**Virtual Initio Programming: WS32 & Ex32 Sample Answers**

**NOTE:** Exercises have become sufficiently complex that quite wide variability in answers can be expected.

**WS32**

**Question 1:** It moves forward until it detects a line with its left line sensor.

**Question 2:** It moves forward until it reaches the square then it prints line\_left Goal Achieved!

**Exercise:**

import bdi.initioagent as cognitive

import time

class EnterAgent(cognitive.InitioAgent):

def \_\_init\_\_(self):

super().\_\_init\_\_()

only\_line\_goal = self.AND(self.G('line\_left'), self.NOT(self.G('obstacle\_right')))

goal\_and\_obstacle = self.AND(self.G('line\_left'), self.b\_obstacle\_centre)

goal\_and\_no\_wall = self.AND(self.G('line\_left'), self.NOT(self.B('obstacle\_right')))

goal\_and\_wall = self.AND(self.G('line\_left'), self.AND(self.B('obstacle\_right'), self.NOT(self.b\_obstacle\_centre)))

self.add\_condition\_rule(goal\_and\_obstacle, self.spin\_left\_rule)

self.add\_condition\_rule(self.G('obstacle\_right'), self.forward\_rule)

self.add\_condition\_rule(goal\_and\_no\_wall, self.spin\_right\_rule)

self.add\_condition\_rule(goal\_and\_wall, self.forward\_rule)

self.add\_goal('line\_left')

self.add\_goal('obstacle\_right')

def b\_obstacle\_centre(self):

if (self.beliefbase['distance'] < 30):

return True

return False

def forward\_rule(self):

self.robot.forward(10)

time.sleep(5)

self.robot.stop()

def spin\_left\_rule(self):

self.robot.spinLeft(10)

time.sleep(1)

self.robot.stop()

def spin\_right\_rule(self):

self.robot.spinRight(10)

time.sleep(1)

**Ex32**

**Exercise 1:**

import bdi.initioagent as cognitive

import random, time

class MachineLearner(cognitive.InitioAgent):

def \_\_init\_\_(self, learning\_rate):

super().\_\_init\_\_()

self.learning\_rate = learning\_rate

self.epsilon = 1

self.actions = ['forward', 'backward', 'left', 'right']

self.dictionary = self.action\_reward(self.actions, 1)

self.rewards = {(1, 1):1, (1, 0):2, (0, 1):0, (0, 0):1}

self.add\_goal('learn\_oval')

self.add\_condition\_rule(self.G('learn\_oval'), self.learn)

self.add\_condition\_rule(self.B('learn\_oval'), self.end\_learning)

def action\_reward(self, action\_list, default):

action\_rewards = {}

for i in range(0, 2):

for j in range(0, 2):

for k in (action\_list):

action\_rewards[((i, j), k)] = default

return action\_rewards

def end\_learning(self):

self.robot.stop()

print(self.dictionary)

self.done()

def get\_max(self, state):

max\_reward = 0

action = 'forward'

for act in self.actions:

if (self.dictionary[(state, act)] > max\_reward):

action = act

max\_reward = self.dictionary[(state, act)]

return action

def action\_execute(self, action):

if (action == "forward"):

self.robot.forward(10)

elif (action == "backward"):

self.robot.reverse(10)

elif (action == "left"):

self.robot.spinLeft(10)

elif (action == "right"):

self.robot.spinRight(10)

else:

self.robot.stop()

def learn(self):

explore = random.random();

state = (self.robot.irLeftLine(), self.robot.irRightLine())

if (explore < self.epsilon):

print("Exploring")

action = random.choice(self.actions)

else:

action = self.get\_max(state)

self.action\_execute(action)

time.sleep(3)

reward = self.rewards[(self.robot.irLeftLine(), self.robot.irRightLine())]

if (reward == 2):

self.epsilon = self.epsilon - 0.05

print("updating epsilon: " + str(self.epsilon))

if (self.epsilon < 0):

self.add\_belief('learn\_oval')

self.dictionary[(state, action)] = self.dictionary[(state, action)] + ( reward - self.dictionary[(state, action)]) \* self.learning\_rate

**Exercise 2:**

import bdi.initioagent as cognitive

import random, time

class MachineLearner(cognitive.InitioAgent):

def \_\_init\_\_(self, learning\_rate):

super().\_\_init\_\_()

self.learning\_rate = learning\_rate

self.epsilon = 1

self.actions = ['forward', 'backward', 'left', 'right']

self.dictionary = self.action\_reward(self.actions, 1)

self.rewards = {(1, 1):1, (1, 0):2, (0, 1):0, (0, 0):1}

self.add\_goal('follow\_oval')

self.add\_condition\_rule(self.G('learn\_oval'), self.learn)

self.add\_condition\_rule(self.AND(self.G('follow\_oval'), self.NOT(self.B('learn\_oval'))), self.first\_learn)

self.add\_condition\_rule(self.AND(self.G('follow\_oval'), self.B('learn\_oval')), self.execute\_best)

def action\_reward(self, action\_list, default):

action\_rewards = {}

for i in range(0, 2):

for j in range(0, 2):

for k in (action\_list):

action\_rewards[((i, j), k)] = default

return action\_rewards

def end\_learning(self):

self.robot.stop()

print(self.dictionary)

self.done()

def get\_max(self, state):

max\_reward = 0

action = 'forward'

for act in self.actions:

if (self.dictionary[(state, act)] > max\_reward):

action = act

max\_reward = self.dictionary[(state, act)]

return action

def action\_execute(self, action):

if (action == "forward"):

self.robot.forward(10)

elif (action == "backward"):

self.robot.reverse(10)

elif (action == "left"):

self.robot.spinLeft(10)

elif (action == "right"):

self.robot.spinRight(10)

else:

self.robot.stop()

def first\_learn(self):

self.add\_goal('learn\_oval')

def execute\_best(self):

state = (self.robot.irLeftLine(), self.robot.irRightLine())

best = self.get\_max(state)

self.action\_execute(best)

def learn(self):

explore = random.random();

state = (self.robot.irLeftLine(), self.robot.irRightLine())

if (explore < self.epsilon):

print("Exploring")

action = random.choice(self.actions)

else:

action = self.get\_max(state)

self.action\_execute(action)

time.sleep(3)

reward = self.rewards[(self.robot.irLeftLine(), self.robot.irRightLine())]

if (reward == 2):

self.epsilon = self.epsilon - 0.05

print("updating epsilon: " + str(self.epsilon))

if (self.epsilon < 0):

self.add\_belief('learn\_oval')

self.dictionary[(state, action)] = self.dictionary[(state, action)] + ( reward - self.dictionary[(state, action)]) \* self.learning\_rate

**Exercise 3:**

import bdi.initioagent as cognitive

import random, time

class ZigZag(cognitive.InitioAgent):

def \_\_init\_\_(self):

super().\_\_init\_\_()

only\_line\_goal = self.AND(self.OR(self.G('line\_left'), self.G('clear')), self.NOT(self.G('obstacle\_right')))

lgoal\_and\_obstacle = self.AND(self.G('line\_left'), self.b\_obstacle\_centre)

lgoal\_and\_no\_wall = self.AND(self.G('line\_left'), self.NOT(self.B('obstacle\_right')))

cgoal\_and\_obstacle = self.AND(self.G('clear'), self.b\_obstacle\_centre)

cgoal\_and\_no\_wall = self.AND(self.G('clear'), self.NOT(self.B('obstacle\_left')))

lgoal\_and\_wall = self.AND(self.G('line\_left'), self.AND(self.B('obstacle\_right'), self.NOT(self.b\_obstacle\_centre)))

cgoal\_and\_wall = self.AND(self.G('clear'), self.AND(self.B('obstacle\_left'), self.NOT(self.b\_obstacle\_centre)))

self.add\_condition\_rule(self.G('end'), self.end)

self.add\_condition\_rule(self.AND(self.B('line\_left'), self.B('clear')), self.remove\_clear)

self.add\_condition\_rule(self.AND(self.NOT(self.G('end')), self.AND(self.NOT(self.G('line\_left')), self.NOT(self.G('clear')))), self.ask)

self.add\_condition\_rule(self.NOT(self.OR(self.B('line\_left'), self.B('clear'))), self.add\_clear)

self.add\_condition\_rule(self.AND(self.G('obstacle\_right'), self.b\_obstacle\_centre), self.spin\_left\_rule)

self.add\_condition\_rule(self.G('obstacle\_right'), self.forward\_rule)

self.add\_condition\_rule(lgoal\_and\_obstacle, self.spin\_left\_rule)

self.add\_condition\_rule(lgoal\_and\_no\_wall, self.forward\_then\_spin\_right\_rule)

self.add\_condition\_rule(cgoal\_and\_obstacle, self.spin\_right\_rule)

self.add\_condition\_rule(cgoal\_and\_no\_wall, self.forward\_then\_spin\_left\_rule)

self.add\_condition\_rule(lgoal\_and\_wall, self.forward\_rule)

self.add\_condition\_rule(cgoal\_and\_wall, self.forward\_rule)

def end(self):

self.add\_belief('end')

self.done()

def ask(self):

self.drop\_belief('end')

goal = input('What would you like me to do? [B]find black,[C]find clear,[E]end')

if (goal == "B"):

self.add\_goal('obstacle\_right')

self.add\_goal('line\_left')

elif (goal == "C"):

self.add\_goal('obstacle\_right')

self.add\_goal('clear')

else:

self.add\_goal('end')

def remove\_clear(self):

print("dropping clear")

self.drop\_belief('clear')

def add\_clear(self):

self.add\_belief('clear')

def forward\_rule(self):

self.robot.forward(10)

time.sleep(5)

self.robot.stop()

def spin\_left\_rule(self):

self.robot.spinLeft(10)

time.sleep(1)

self.robot.stop()

def spin\_right\_rule(self):

self.robot.spinRight(10)

time.sleep(1)

self.robot.stop()

def forward\_then\_spin\_left\_rule(self):

self.robot.forward(10)

time.sleep(1)

self.robot.spinLeft(10)

time.sleep(2)

self.robot.stop()

def forward\_then\_spin\_right\_rule(self):

self.robot.forward(10)

time.sleep(1)

self.robot.spinRight(10)

time.sleep(2)

self.robot.stop()

def b\_obstacle\_centre(self):

if (self.beliefbase['distance'] < 30):

return True

return False



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