

Classical planning deals with finding a sequence of actions transferring the initial state of world into a desired goal state. This work surveys two classical planning techniques, forward and backward search. We implement both techniques in a form of software prototype using five different search algorithms, in particular DFS, BFS, IDDFS, A*, WA*. By introducing additional heuristic we get family of 26 planners. We compare efficiency of the planners on several domains from International Planning Competition. None of the planners is significantly better on all domains, however, in general, the planners based on forward search perform better.