MULTI-AGENT NAVIGATION

MULTI-AGENT NAVIGATION

- Why do it?
  - Autonomous cars
  - Robot assembly lines
  - Swarm simulation
  - Pedestrian simulation

STATIC PLANNING

- Identifying and encoding traversable space
  - Roadmaps
  - Navigation Mesh
  - Corridor Maps
  - Guidance/potential fields

STATIC PLANNING

- Graph searches
  - Many of the most common structures are, ultimately, graphs
  - Finding paths from start to end become a basic operation
  - Let’s look at path computation
  - http://www.youtube.com/watch?v=czk4xgdhdY4
  - http://www.youtube.com/watch?v=nDyGEq_ugGo

OPTIMAL PATH

- Typically, we're looking not for *any* path
- We have a sense of "optimality" and want to find the optimal path.
  - Typically distance
- Can be other functions: e.g.,
  - Energy consumed (such as for uneven terrain)
  - Psychological comfort (avoiding "negative" regions)

OPTIMAL PATH

- The roadmap (and all graph-based traversal structures) encode the *costs* of moving from one node to another.
  - Cost of movement is the *edge weight*.
- Given graph and optimality definition, how do we compute the optimal path?

OPTIMAL PATH

- Assumptions
  - The edge weights are non-negative
    - i.e., every section of the path requires a “cost”
    - No path section provides a “gain”

BREADTH/DEPTH-FIRST SEARCHES

- Depth-first
  - Similar to wall-following algorithms
- Breadth-first
  - Weights are ignored, the boundary of the search space is all nodes *k* steps away from the source.
- This is guaranteed to find *a* path if one exists
- Only guaranteed to be optimal if it is the only path

DJIKSTRA’S ALGORITHM

- Single-source shortest-path (to all other nodes)
  - Shortest path to a specific target node is simply an early termination
  - Djikstra’s Algorithm requires our non-negative cost assumption
  - What is the algorithm?

Dijkstra, E. W. (1959). "A note on two problems in connexion with graphs". Numerische Mathematik 1: 269–271. doi:10.1007/BF01386390

DJIKSTRA'S ALGORITHM

```
minDistance( start, end, nodes )
   For all nodes n_i, i≠ start , cost(n_i) = ∞
   cost( start ) = 0
   unvisited = nodes \ {start}  // set
                                   // difference
   c = start                      // current node
   while ( true )
      if ( c == end ) return cost(c)
      For each unvisited neighbor, n, of c
         cost(n) = min( cost(n), cost(c) + E(c,n)
           )
      c = minCost( unvisited )    // 1
      if ( cost( c ) == ∞ ) return ∞
```

Why?

1) We'll say that minCost returns ∞ if there are no nodes in the set.

DJIKSTRA'S ALGORITHM

- How do we modify it to get a path?
- What is the cost of this algorithm?

DJIKSTRA'S ALGORITHM

```
shortestPath( start, end, nodes )
    For all nodes n_i, i≠ start
        cost(n_i) = ∞
        prev(n_i) = Ø
    cost( start ) = 0
    unvisited = nodes \ {start}  # set difference
    visited = {}
    c = start# current node
    while ( true )
        if ( c == end ) break
        For each unvisited neighbor, n, of c
            if ( cost(n) > cost(c) + E(c,n) )
            cost(n) = cost(c) + E(c,n)
            prev(n) = c
        c = minCost( unvisited )
        if ( cost( c ) == ∞ ) break
    if ( cost(end) < ∞ )
        construct path
```

DJIKSTRA'S ALGORITHM

- Constructing a path

```
path = [ end ]
p = prev[ end ]
while (p != Ø)
   path = [ p ] + path      // list concatenation
   p = prev[ p ]
return path
```

DJIKSTRA'S ALGORITHM

- What is the cost of this algorithm?
- If the graph has V vertices and E edges:
  - E * d + V * m
    - d is the cost to change a node's cost
    - m is the cost to extract the *minimum* unvisited node
  - d is typically a nominal constant
  - m depends on how we find the minimum node

DJIKSTRA'S ALGORITHM

- Minimum neighbor
  - Djikstra originally did a search through a list
    - Maintaining a sorted vector doesn't solve the problem
    - The cost of maintaining the sort would be the same as simply searching
    - Cost was $|E| + |V|^2$

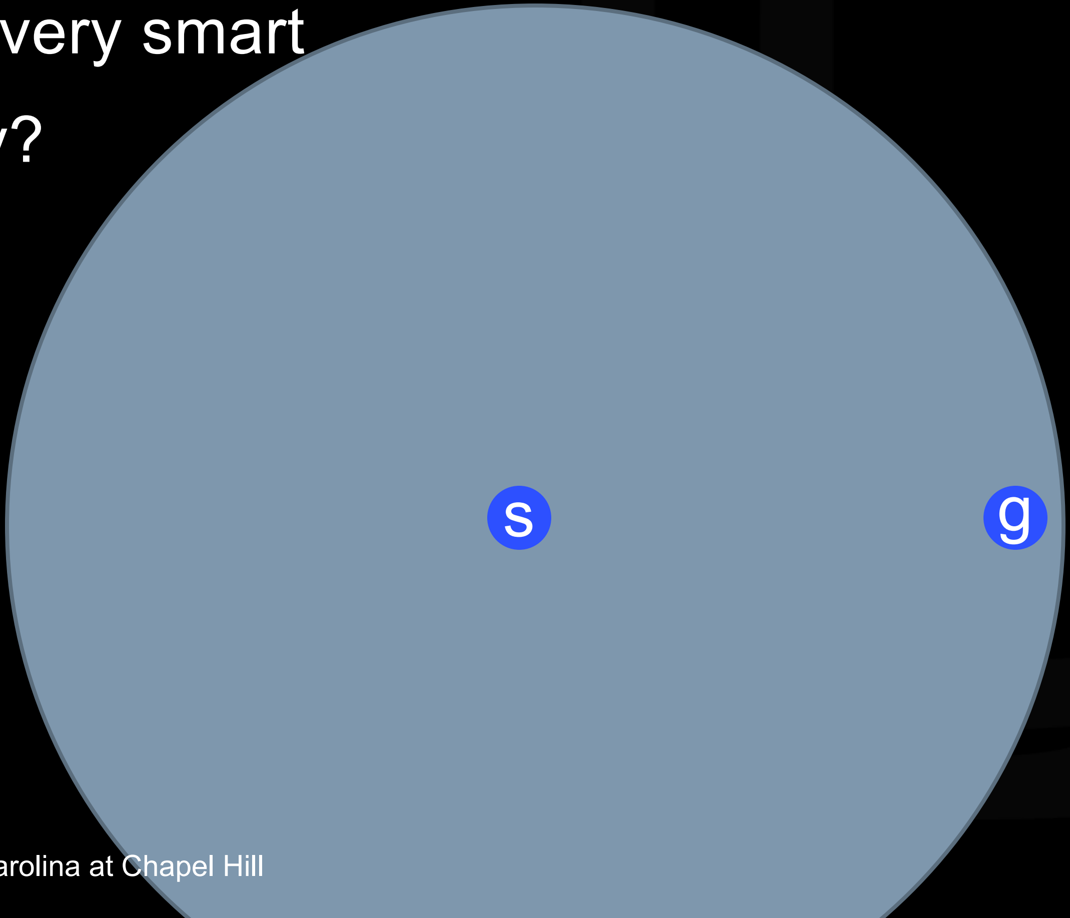
DJIKSTRA'S ALGORITHM

- Minimum neighbor
  - Use a good min-heap implementation and it becomes
    - |E| + |V| log |V|
  - (Good → Fibonnaci heap)

Fredman, Michael Lawrence; Tarjan, Robert E. (1984). "Fibonacci heaps and their uses in improved network optimization algorithms". 25th Annual Symposium on Foundations of Computer Science. IEEE. pp. 338–346. doi:10.1109/SFCS.1984.715934

DJIKSTRA'S ALGORITHM

- Good *general* solution
  - Guaranteed to find optimal solution
  - Not very smart
  - Why?



DJIKSTRA’S ALGORITHM

- Djikstra’s algorithm expands the front uniformly
  - It extends the *nearest* node on the front
  - This causes the search space to inflate uniformly

A* ALGORITHM

- "Best-first" graph search algorithm
  - Uses a knowledgeable heuristic to estimate the cost of a node
  - At any given time, the *expected* cost of a node, f(x), is the sum of two terms
    - Its known cost from the start, g(x)
    - Its estimated cost to the goal, h(x)

Hart, P. E.; Nilsson, N. J.; Raphael, B. (1968). "A Formal Basis for the Heuristic Determination of Minimum Cost Paths". IEEE Transactions on Systems Science and Cybernetics SSC4 4 (2): 100–107. doi:10.1109/TSSC.1968.300136

A* ALGORITHM

- Admissible heuristics
  - $h(x) \leq D(x,goal)$
    - $D(x,y)$ actual distance from node x to y
    - i.e., it must be a *conservative* estimate
  - In path planning, our heuristic is usually Euclidian distance
    - Triangle-inequality insures admissibility
  - $h(x) \leq E(x,y) + h(y)$

A* ALGORITHM

- Admissible heuristics
  - Monotonic/consistent
    - $h(x) \leq E(x,y) + h(y)$
    - i.e., the “best guess” for a node *cannot* be beaten by the known cost to move to another node and my best guess from there
    - This applies to our Euclidian distance heuristic

A* ALGORITHM

```
minDistance( start, end, nodes )
    closed = {}
    open = {start}
    g[ start ] = 0
    f[ start ] = g[ start ] + h( start, end )
    while ( ! open.isEmpty() )
        c = minF( open )
        if ( c == end ) return g[ c ]
        open = open \ {c}; closed = closed U {c}
        for each neighbor, n, of c
            gTest = g[ c ] + E( n, c )
            fTest = gTest = h( n, e )
            if ( n in closed && fTest ≥ f[ n ] ) continue
            if ( n not in open || fTest < f[n] )
                g[ n ] = gTest
                f[ n ] = fTest
                open = open U {n}
```

Wikipedia's A* - assumes monotonic heuristic

A* ALGORITHM

- Closed set
  - It is (apparently) possible to visit a node but then later need to place it back in the open set.
    - $f(n) = g(n) + h(n,e)$
    - $h(n, e)$ is constant for constant n & e
    - So, to revisit n, $f'(n) < f(n) \rightarrow g'(n) < g(n)$
    - We found a SHORTER path to that node

A* ALGORITHM

```
minDistance( start, end, nodes )
    closed = {}
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    g[ start ] = 0
    f[ start ] = g[ start ] + h( start, end )
    while ( ! open.isEmpty() )
        c = minF( open )
        if ( c == end ) return g[ c ]
        open = open \ {c}; closed = closed U {c}
        for each neighbor, n, of c
            if ( n in closed ) continue
            gTest = g[ c ] + E( n, c )
            if ( gTest < g[ n ] )
                g[ n ] = gTest; f[ n ] = gTest + h(n, end)
            open = open U {n}
```

Sean's A*

A* ALGORITHM

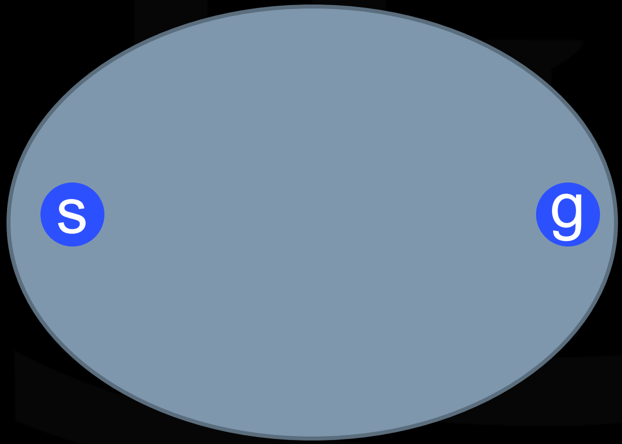
- Notes
  - The goal node may be visited/updated multiple times
    - There may be multiple paths to it
  - Only when the goal node is the “closest” node is it considered final
  - Like Djikstra’s, it will still fall victim to local minima
    - But gets around them more efficiently

A* ALGORITHM

- Constructing a path
  - We add the same instrumentation
    - Record where we came from when we reduce the cost of each node
    - Construct the path by tracing backwards from the goal

A* ALGORITHM

- Efficient solution
  - Guaranteed to find optimal solution (for admissible heuristic)
  - Much more optimized search space
    - Can be fooled by adversarial graph

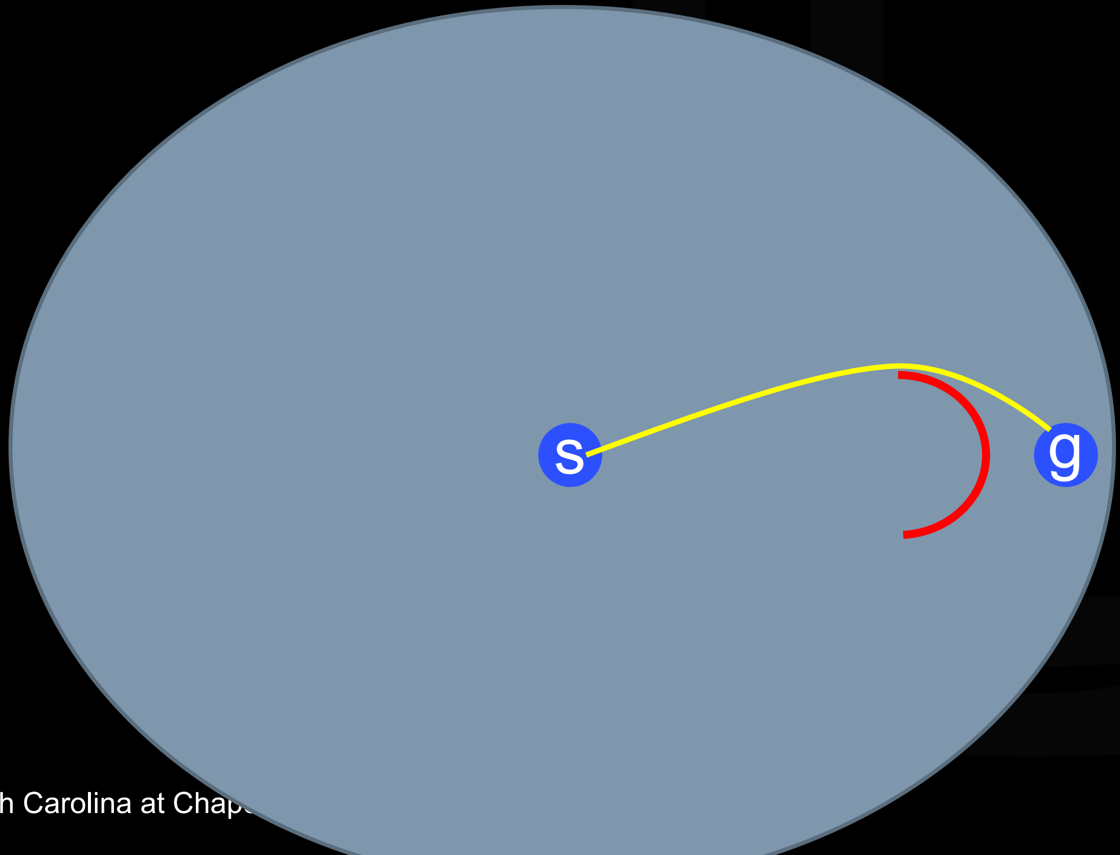


A* ALGORITHM

- Demos
  - http://www.youtube.com/watch?v=DINCL5cd_w0

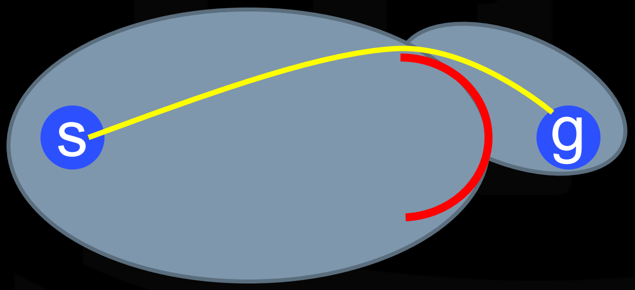
WEIGHTED A* ALGORITHM

- $f(n) = g(n) + \varepsilon h(n)$
  - $\varepsilon = 0 \rightarrow$ Djikstra's algorithm



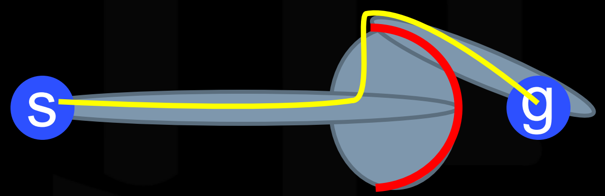
WEIGHTED A* ALGORITHM

- $f(n) = g(n) + \varepsilon h(n)$
  - $\varepsilon = 1 \rightarrow$ A* algorithm



WEIGHTED A* ALGORITHM

- $f(n) = g(n) + \varepsilon h(n)$
  - $\varepsilon > 1 \rightarrow$ Strong bias straight towards goal
  - Trades optimality for speed
    - Cost of path $\leq \varepsilon$ * cost of optimal



D* ALGORITHM

- These algorithms assume perfect *a priori* knowledge of the environment.
- What if our knowledge of the environment (or the environment itself) changes over time?
- We use an incremental search algorithm
- D*, D*lite, etc.
- These algorithms used in the Mars rovers and the DARPA grand challenge winners

Stentz, Anthony (1994), "Optimal and Efficient Path Planning for Partially-Known Environments", Proceedings of the International Conference on Robotics and Automation: 3310–3317

QUESTIONS?

MULTI-AGENT NAVIGATION

- Planning for multiple robots
  - *Can* be the same as for a single robot with multiple parts
    - The parts need not be connected
  - Dimension grows linearly with the robots
    - For N simple 2D, translational robots, there are 2N dimensions in configuration space
    - Algorithmic complexity tends to be exponential in dimensions (for “complete” solutions)

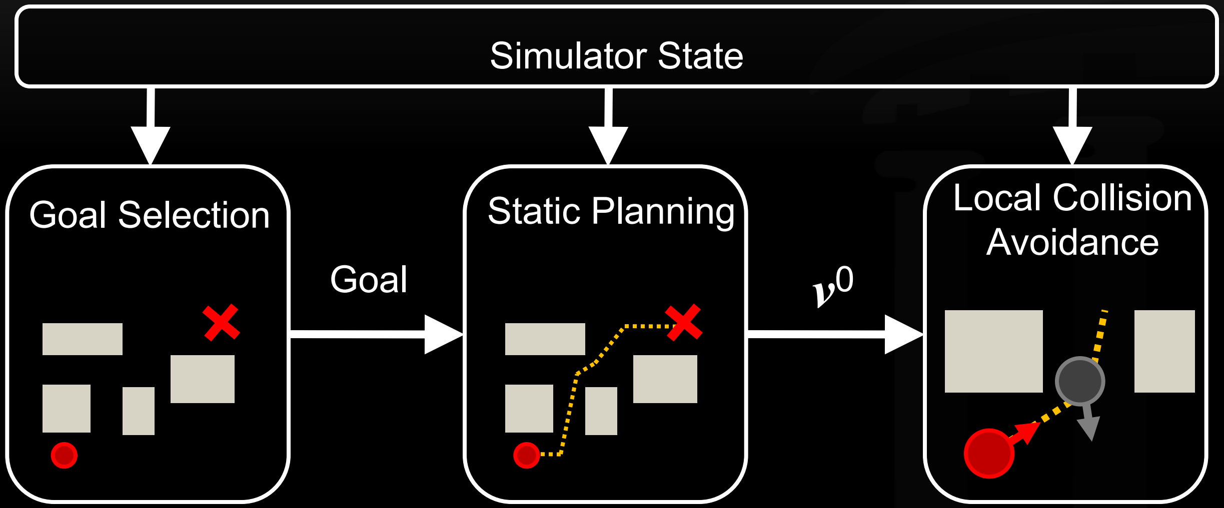
MULTI-AGENT NAVIGATION

- How do we do it?
  - Complete solutions are infeasible
  - “Decoupled” solutions
    - Independent solutions whose interactions are coordinated
    - Computational necessity
    - Design decision
      - Entities are often independent

MULTI-AGENT NAVIGATION

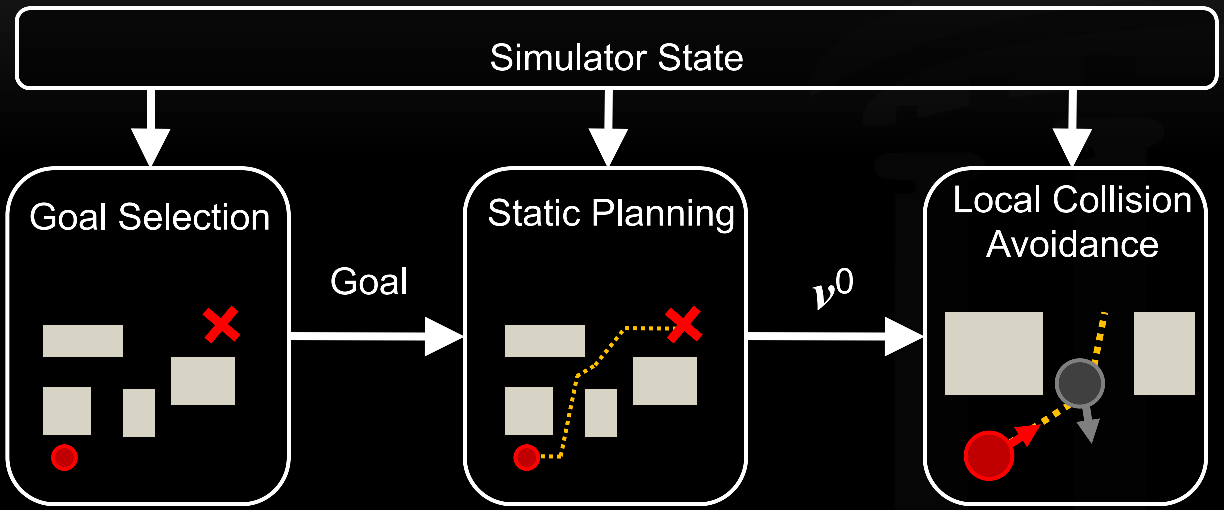
- Skipping general multi-agent navigation
  - Path coordination
  - Pareto optimality
  - Prioritized planning
  - We’ll come back to it
- Focus on pedestrian/crowd simulation

PEDESTRIAN SIMULATOR ARCHITECTURE



- Simulation State: obstacles (static & dynamic), agents
- Goal Selection: High-order model of what the agent wants
- Static Planning: Plan to reach goal vs. *static* obstacles
- Local Collision Avoidance: Adapt plan because of other agents

PEDESTRIAN SIMULATOR ARCHITECTURE



- We'll have two homework assignments
  - Implement static planning algorithm
  - Implement local collision avoidance