

Artificial Intelligence in Robotics

Lecture 10: Patrolling

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Mathematical programming

LP

$$\begin{array}{ll} \text{maximize} & \mathbf{c}^T \mathbf{x} \\ \text{subject to} & A\mathbf{x} \leq \mathbf{b} \\ \text{and} & \mathbf{x} \geq \mathbf{0} \end{array}$$

MILP

Some of the variables are integer

Objective and constraints are still linear

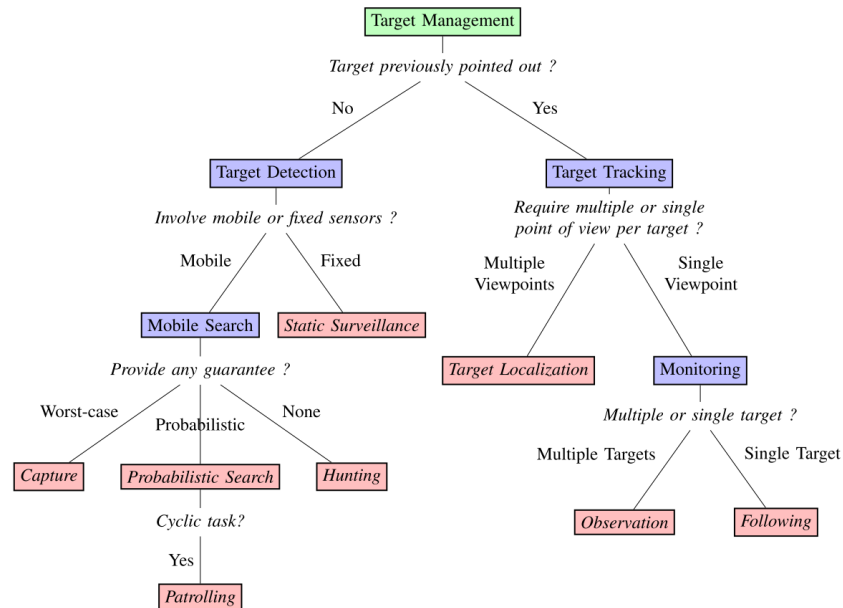
Convex program

Optimize a convex function over a convex set

Non-convex program

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Task Taxonomy



Robin, C., & Lacroix, S. (2016). Multi-robot target detection and tracking: taxonomy and survey. *Autonomous Robots*, 40(4), 729–760.

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Resource allocation games

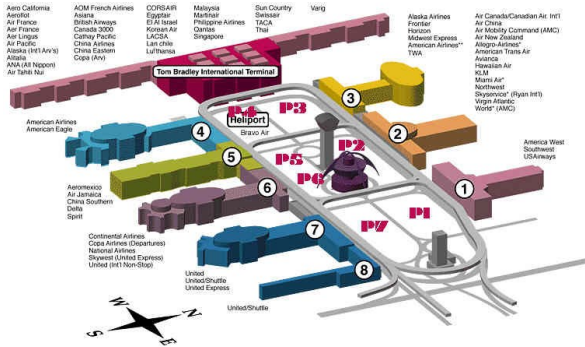
Developed by team of prof. M. Tambe at USC (2008-now)

In daily use by various organizations and security agencies



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Resource allocation games



	①	②	③	④	⑤	⑥	⑦	⑧	
Unprotected	10	11	9	15	11	15	14	6	-15
Protected	5	4	5	7	6	5	7	3	-14
Optimal strategy	0	0.14	0	0.62	0.2	0.49	0.56	0	-11
									-10

Resource allocation games



Set of targets: $T = t_1, \dots, t_n$

Limited (homogeneous) security resources $r \in \mathbb{N}$

Each resource can fully protect (cover) a single target

The attacker attacks a single target

Attacker's utility for covered/uncovered attack: $U_a^c(t) < U_a^u(t)$

Defender's utility for covered/uncovered attack: $U_d^c(t) > U_d^u(t)$

Stackelberg equilibrium



the leader (l) – publicly commits to a strategy
 the follower (f) – plays a best response to leader



$$\arg \max_{\sigma_l \in \Delta(A_l)} \max_{\sigma_f \in BR_f(\sigma_l)} r_l(\sigma_l, \sigma_f)$$

Example

	L	R
U	(4,2)	(6,1)
D	(3,1)	(5,2)

Why?

The defender needs to commit in practice (laws, regulations, etc.)

It may lead to better expected utility

NE: (U,L) -> 4; Pure SE: (D,R) -> 5; Mixed SE ~ 5.5

Mixed Stackelberg equilibrium



	L	R
U	(4,2)	(6,1)
D	(3,1)	(5,2)

Strong Stackelberg Equilibrium

Follower breaks ties in favor of the leader (0.5; 0.5) -> 5.5

Form many settings can be motivated by infinitesimal deviation

Weak Stackelberg Equilibrium

Follower breaks ties worst for the leader (0.5; 0.5) -> 3.5

The equilibrium may not exist, because smaller motivation is better

Solving resource allocation games

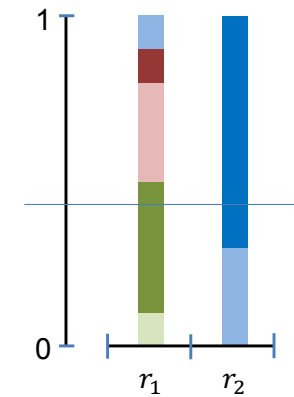
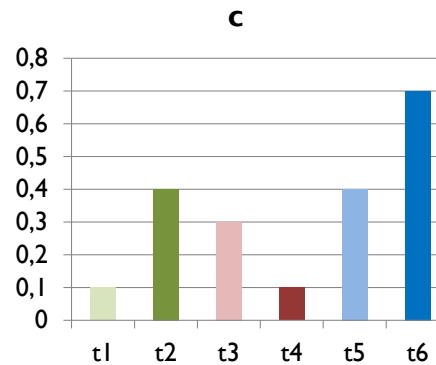


Kiekintveld, et al.: Computing Optimal Randomized Resource Allocations for Massive Security Games, AAMAS 2009

Only coverage vector c_t matters, Z is a sufficiently large number

$$\begin{aligned} \max \quad & d \\ a_t \in \quad & \{0, 1\} \quad \forall t \in T \\ \sum_{t \in T} a_t = \quad & 1 \\ c_t \in \quad & [0, 1] \quad \forall t \in T \\ \sum_{t \in T} c_t \leq \quad & m \\ d - U_{\Theta}(t, C) \leq \quad & (1 - a_t) \cdot Z \quad \forall t \in T \\ 0 \leq k - U_{\Psi}(t, C) \leq \quad & (1 - a_t) \cdot Z \quad \forall t \in T \end{aligned}$$

Sampling the coverage vector

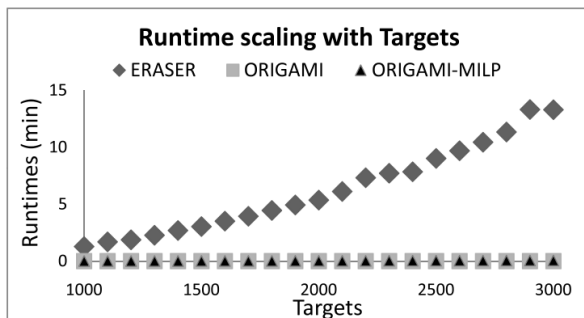


Scalability



25 resources, 3000 targets $\Rightarrow 5 \times 10^{61}$ defender's actions
no chance for matrix game representation

The algorithm explained above is ERASER



Studied extensions



Complex structured defender strategies



Probabilistically failing actions



Attacker's types



Resource types and teams



Bounded rational attackers

Agmon et al.: Multi-Robot Adversarial Patrolling: Facing a Full-Knowledge Opponent. JAIR 2011.



The attacker can see the patrol!

Advantages

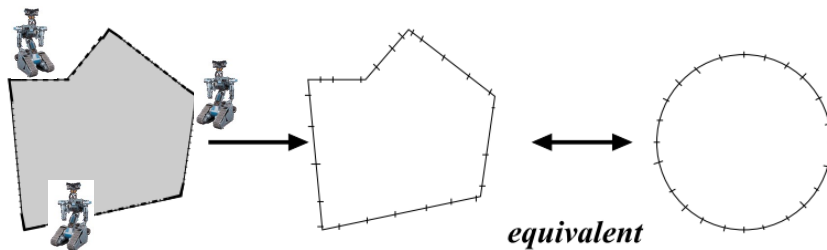
- Wide existing literature (many variations)
- Good scalability
- Real world deployments

Limitation

The attacker cannot react to observations (e.g., defender's position)

Perimeter patrolling

Polygon P , perimeter split to N segments



Defender has homogenous resources $k > 1$

- move 1 segment per time step
- turn to the opposite direction in τ time steps

Attacker can wait infinitely long and sees everything

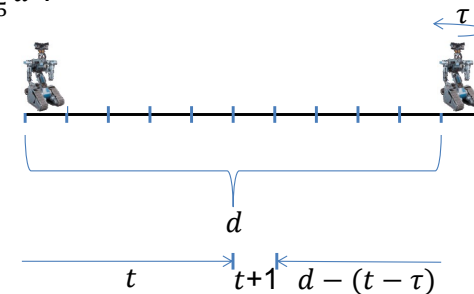
- chooses a segment where to attack
- requires t time steps to penetrate

Interesting parameter settings

Let $d = \frac{N}{k}$ be the distance between equidistant robots

There is a perfect deterministic patrol strategy if $t \geq d$
the robots can just continue in one direction

What about $t = \frac{4}{5}d$?



The attacker can guarantee success if $t + 1 < d - (t - \tau) \Rightarrow t < \frac{d + \tau - 1}{2}$

Optimal patrolling strategy



Class of strategies: continue with probability p , else turn around

Theorem: In the optimal strategy, all robots are equidistant and face in the same direction.

Proof sketch:

1. the probability of visiting the worst case segment between robots decreases with increasing distance between the robots
2. making a move in different directions increases the distance

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Probability of penetration

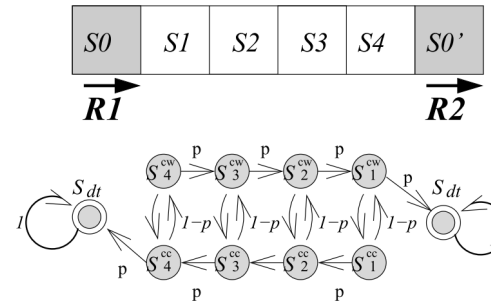


For simplicity assume $\tau = 1$

Probability of visiting s_i at least once in next t steps

= probability of visiting the absorbing end state from s_i

sum of each direction visited separately



	S_1^{cc}	S_1^{cw}	S_2^{cc}	S_2^{cw}	S_3^{cc}	S_3^{cw}	S_4^{cc}	S_4^{cw}	S_{dt}
S_1^{cc}	0	$1-p$	p	0	0	0	0	0	0
S_1^{cw}	$1-p$	0	0	0	0	0	0	0	p
S_2^{cc}	0	0	0	$1-p$	p	0	0	0	0
S_2^{cw}	0	p	$1-p$	0	0	0	0	0	0
S_3^{cc}	0	0	0	0	0	$1-p$	p	0	0
S_3^{cw}	0	0	0	p	$1-p$	0	0	0	0
S_4^{cc}	0	0	0	0	0	0	0	$1-p$	p
S_4^{cw}	0	0	0	0	0	p	$1-p$	0	0
S_{dt}	0	0	0	0	0	0	0	0	1

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Probability of penetration



Algorithm 1 Algorithm FindFunc(d, t)

- 1: Create matrix M of size $(2d + 1)(2d + 1)$, initialized with 0s
- 2: Fill out all entries in M as follows:
- 3: $M[2d + 1, 2d + 1] = 1$
- 4: **for** $i \leftarrow 1$ to $2d$ **do**
- 5: $M[i, \max\{i + 1, 2d + 1\}] = p$
- 6: $M[i, \min\{1, i - 2\}] = 1 - p$
- 7: Compute $MT = M^t$
- 8: Res = vector of size d initialized with 0s
- 9: **for** $1 \leq loc \leq d$ **do**
- 10: V = vector of size $2d + 1$ initialized with 0s.
- 11: $V[2loc] \leftarrow 1$
- 12: $Res[loc] = V \times MT[2d + 1]$
- 13: Return Res

All computations are symbolic. The result are functions $ppd_i: [0,1] \rightarrow [0,1]$ expressing the probability of penetration at i for a given probability of turn.

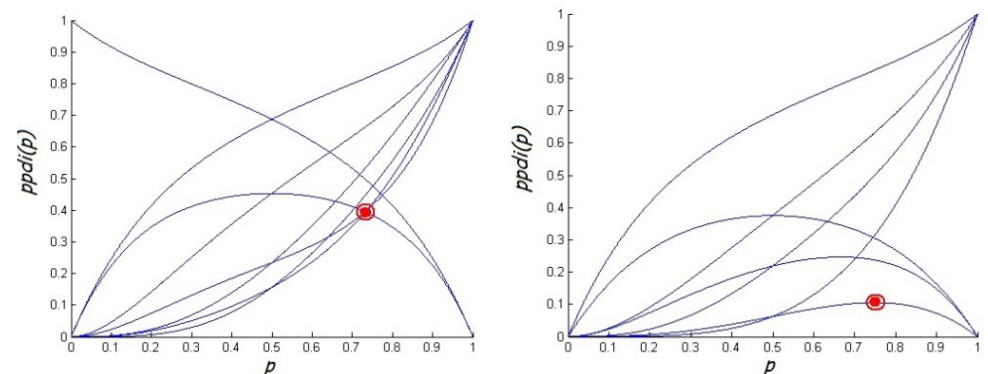
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Optimal turn probability



Maximin value for p

Each line represents one segment (ppd_i)



Iterate all pairs of intersection and maximal points to find solution

it is all polynomials

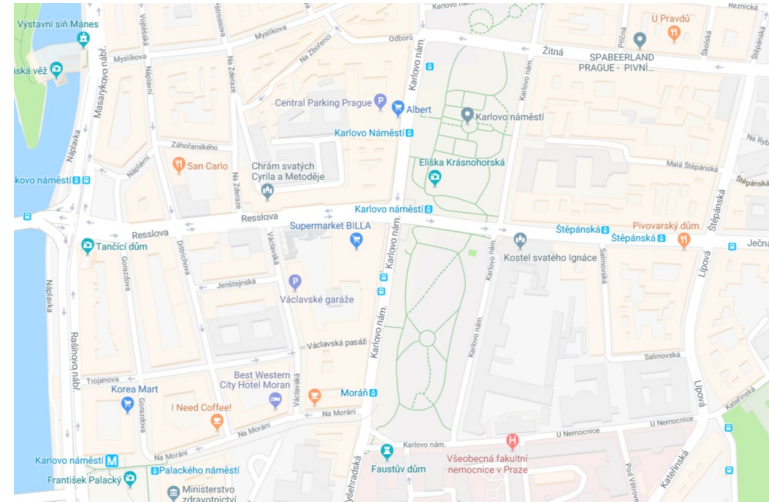
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- Split the perimeter to segments traversable in unit time
- Distribute patrollers uniformly along the perimeter
- Coordinate them to always face the same way
- Continue with probability p turn around with probability $(1 - p)$



Basilico et al.: Patrolling security games: Definition and algorithms for solving large instances with single patroller and single intruder. AIJ 2012.



Area patrolling - Formal model

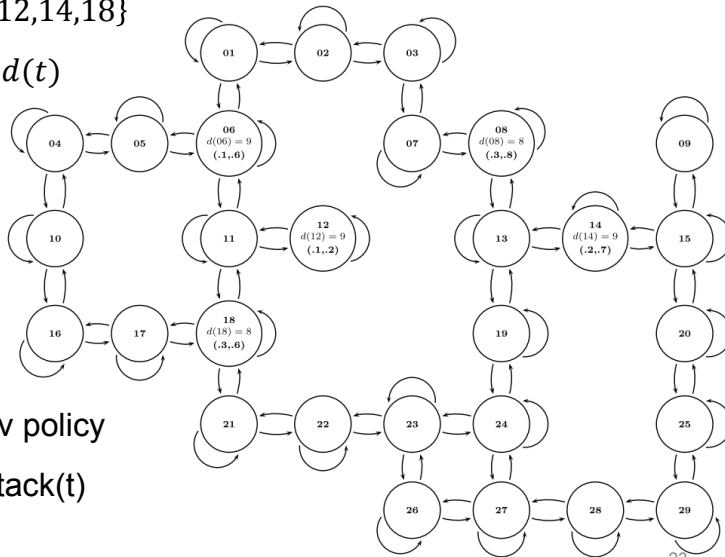


Environment represented as a graph

Targets $T = \{6,8,12,14,18\}$

Penetration time $d(t)$

Target values
 $(v_d(t), v_a(t))$



Defender: Markov policy

Attacker: wait, attack(t)

Solving zero-sum patrolling game



We assume $\forall t \in T : v_a(t) = v_d(t)$

$a(i, j) = 1$ if the patrol can move from i to j in one step; else 0

$P_c(t, h)$ is the probability of stopping an attack at target t started when the patrol was at node h

$\gamma_{i,j}^{w,t}$ is the probability that the patrol reaches node j from i in w steps without visiting target t

max u

$$\alpha_{i,j} \geq 0 \quad \forall i, j \in V$$

$$\sum_{j \in V} \alpha_{i,j} = 1 \quad \forall i \in V$$

$$\alpha_{i,j} \leq a(i, j) \quad \forall i, j \in V$$

$$\gamma_{i,j}^{1,t} = \alpha_{i,j} \quad \forall t \in T, i, j \in V \setminus \{t\}$$

$$\gamma_{i,j}^{w,t} = \sum_{x \in V \setminus \{t\}} (\gamma_{i,x}^{w-1,t} \alpha_{x,j}) \quad \forall w \in \{2, \dots, d(t)\}, t \in T, i, j \in V \setminus \{t\}$$

$$P_c(t, h) = 1 - \sum_{j \in V \setminus \{t\}} \gamma_{h,j}^{d(t),t} \quad \forall t \in T, h \in V$$

$$u \leq u_d(\text{intruder-capture}) P_c(t, h) + u_d(\text{penetration-t})(1 - P_c(t, h))$$

$\alpha_{i,j}$ is the probability of moving from i to j

$$u_d(x) = \begin{cases} \sum_{i \in T} v_d(i), & x = \text{intruder-capture or no-attack} \\ \sum_{i \in T \setminus \{t\}} v_d(i), & x = \text{penetration-t} \end{cases}$$

What type of optimization problem is this? LP? MILP? Convex?

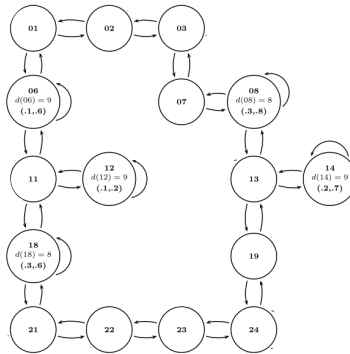
Scaling up



No need to visit nodes not on shortest paths between targets

With multiple shortest paths, only the closer to targets is relevant

It is suboptimal to stay at a node that is not a target



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Summary



GT can be applied to real world problems in robotics

Pursuit-evasion games

- Perfect information capture

- Visibility-based tracking

- Patrolling

 - resource allocation

 - perimeter patrolling

 - area patrolling

AI (GT) problems can often be solved by transformation to mathematical programming

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Resources



Kiekintveld, C., Jain, M., Tsai, J., Pita, J., Ordóñez, F. and Tambe, M. "Computing optimal randomized resource allocations for massive security games." AAMAS 2009.

Agmon, Noa, Gal A. Kaminka, and Sarit Kraus. "Multi-robot adversarial patrolling: facing a full-knowledge opponent." Journal of Artificial Intelligence Research 42 (2011): 887-916.

Basilico, Nicola, Nicola Gatti, and Francesco Amigoni. "Patrolling security games: Definition and algorithms for solving large instances with single patroller and single intruder." Artificial Intelligence 184 (2012): 78-123.

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