

# Path Planning

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Lecture 03

B4M36UIR – Artificial Intelligence in Robotics



## Overview of the Lecture

- Part 1 – Path Planning
  - Introduction to Path Planning
  - Notation and Terminology
  - Path Planning Methods
- Part 2 – Grid and Graph based Path Planning Methods
  - Grid-based Planning
  - DT for Path Planning
  - Graph Search Algorithms
  - D\* Lite
  - Path Planning based on Reaction-Diffusion Process



## Part I

### Part 1 – Path and Motion Planning



## Robot Motion Planning – Motivational problem

- How to transform high-level task specification (provided by humans) into a low-level description suitable for controlling the actuators?

*To develop **algorithms** for such a transformation.*

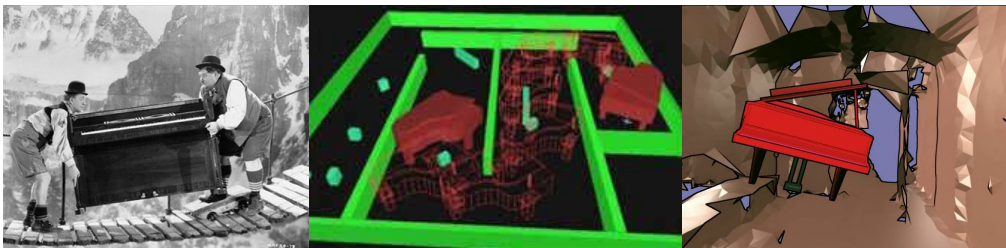
The motion planning algorithms provide transformations how to move a robot (object) considering all operational constraints.



## Piano Mover's Problem

*A classical motion planning problem*

Having a CAD model of the piano, model of the environment, the problem is how to move the piano from one place to another without hitting anything.



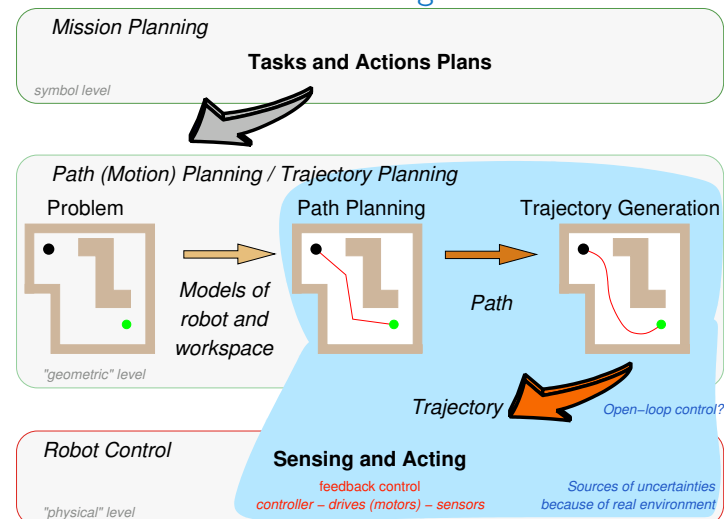
*Basic motion planning algorithms are focused primarily on rotations and translations.*

- We need **notion** of model representations and formal definition of the problem.
- Moreover, we also need a context about the problem and **realistic assumptions**.

*The plans have to be admissible and feasible.*



## Robotic Planning Context



## Real Mobile Robots

In a real deployment, the problem is more complex.

- The world is changing.
- Robots update the knowledge about the environment.

*localization, mapping and navigation*

- New decisions have to be made based on the feedback from the environment.

*Motion planning is a part of the mission re-planning loop.*



*Josef Štrunc, Bachelor thesis, CTU, 2009.*

An example of **robotic mission**:

Multi-robot exploration of unknown environment.

**How to deal with real-world complexity?**

*Relaxing constraints and considering realistic assumptions.*



## Notation

- $\mathcal{W}$  – **World model** describes the robot workspace and its boundary determines the obstacles  $\mathcal{O}_i$ .

*2D world,  $\mathcal{W} = \mathbb{R}^2$*

- A **Robot** is defined by its geometry, parameters (kinematics) and it is controllable by the motion plan.

- $\mathcal{C}$  – **Configuration space (C-space)**

A concept to describe possible configurations of the robot. The robot's **configuration** completely specify the robot location in  $\mathcal{W}$  including specification of all degrees of freedom.

*E.g., a robot with rigid body in a plane  $\mathcal{C} = \{x, y, \varphi\} = \mathbb{R}^2 \times S^1$ .*

- Let  $\mathcal{A}$  be a subset of  $\mathcal{W}$  occupied by the robot,  $\mathcal{A} = \mathcal{A}(q)$ .
- A subset of  $\mathcal{C}$  occupied by obstacles is

$$\mathcal{C}_{obs} = \{q \in \mathcal{C} : \mathcal{A}(q) \cap \mathcal{O}_i, \forall i\}.$$

- **Collision-free configurations** are

$$\mathcal{C}_{free} = \mathcal{C} \setminus \mathcal{C}_{obs}.$$



## Path / Motion Planning Problem

- **Path** is a continuous mapping in  $\mathcal{C}$ -space such that

$$\pi : [0, 1] \rightarrow \mathcal{C}_{free}, \text{ with } \pi(0) = q_0, \text{ and } \pi(1) = q_f.$$

- **Trajectory** is a path with explicit parametrization of time, e.g., accompanied by a description of the motion laws ( $\gamma : [0, 1] \rightarrow \mathcal{U}$ , where  $\mathcal{U}$  is robot's action space).

$$[T_0, T_f] \ni t \rightsquigarrow \tau \in [0, 1] : q(t) = \pi(\tau) \in \mathcal{C}_{free} \quad \text{It includes dynamics.}$$

The path planning is the determination of the function  $\pi(\cdot)$ .

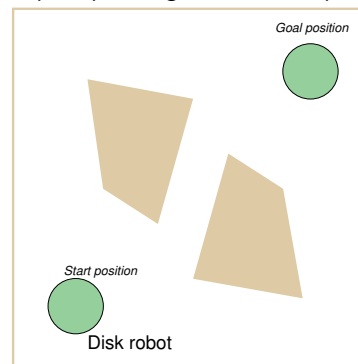
Additional requirements can be given:

- **Smoothness** of the path;
- **Kinodynamic constraints**, e.g., considering friction forces;
- **Optimality criterion** – shortest vs fastest (length vs curvature).
- **Path planning** – planning a collision-free path in  $\mathcal{C}$ -space.
- **Motion planning** – planning collision-free motion in the **state space**.

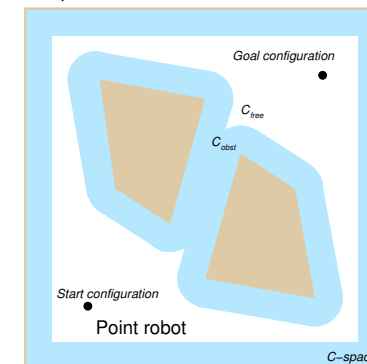


## Planning in $\mathcal{C}$ -space

Robot path planning for a disk-shaped robot with a radius  $\rho$ .



Motion planning problem in geometrical representation of  $\mathcal{W}$ .



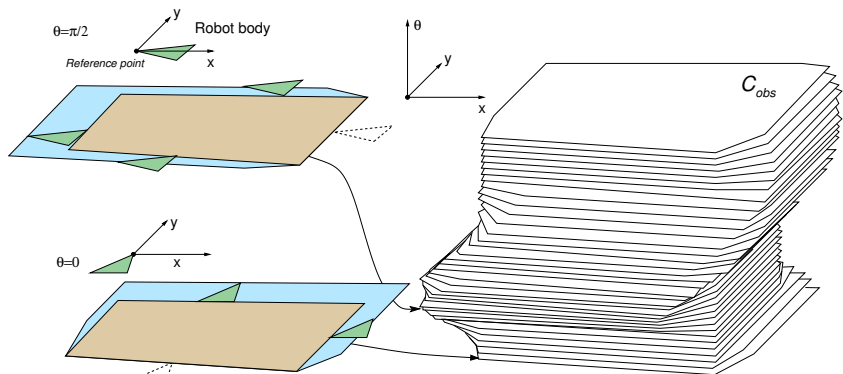
Motion planning problem in  $\mathcal{C}$ -space representation.

$\mathcal{C}$ -space has been obtained by enlarging obstacles by the disk  $\mathcal{A}$  with the radius  $\rho$ .

By applying Minkowski sum:  $\mathcal{O} \oplus \mathcal{A} = \{x + y \mid x \in \mathcal{O}, y \in \mathcal{A}\}$ .



## Example of $\mathcal{C}_{obs}$ for a Robot with Rotation



A simple 2D obstacle  $\rightarrow$  has a complicated  $\mathcal{C}_{obs}$ .

- Deterministic algorithms exist.

Requires exponential time in  $\mathcal{C}$  dimension, J. Canny, PAMI, 8(2):200–209, 1986.

- Explicit representation of  $\mathcal{C}_{free}$  is impractical to compute.



## Representation of $\mathcal{C}$ -space

How to deal with continuous representation of  $\mathcal{C}$ -space?

### Continuous Representation of $\mathcal{C}$ -space

#### Discretization

processing critical geometric events, (random) sampling  
roadmaps, cell decomposition, potential field

#### Graph Search Techniques

BFS, Gradient Search, A\*



# Planning Methods - Overview

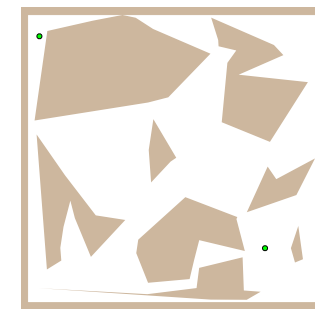
(selected approaches)

- **Point-to-point** path/motion planning. *Multi-goal path/motion/trajectory planning later*
- **Roadmap based methods** – Create a connectivity graph of the free space. *(Complete but impractical)*
  - Visibility graph;
  - Cell decomposition;
  - Voronoi graph.
- Discretization into a **grid-based** (or lattice-based) representation *(Resolution complete)*
- **Potential field methods** *(Complete only for a "navigation function", which is hard to compute in general)*  
*Classic path planning algorithms*
- **Randomized sampling-based methods**
  - Creates a roadmap from connected random samples in  $C_{free}$ .
  - Probabilistic roadmaps. *Samples are drawn from some distribution.*
  - Very successful in practice.

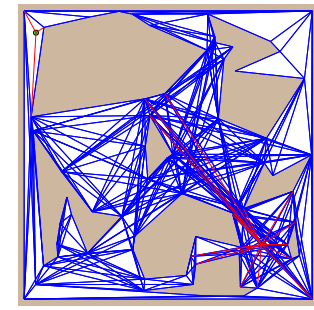


# Visibility Graph

1. Compute visibility graph.
2. Find the shortest path.

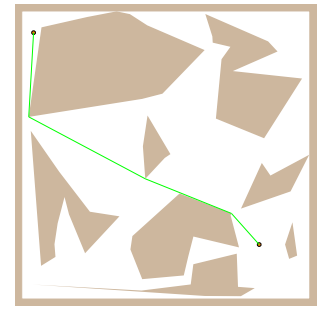


Problem



Visibility graph

E.g., by Dijkstra's algorithm.



Found shortest path

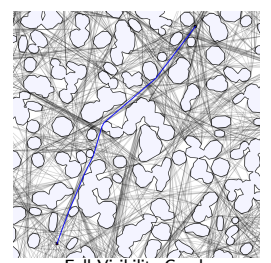
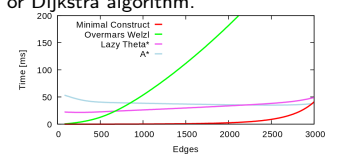
Constructions of the visibility graph:

- Naïve – all segments between  $n$  vertices of the map  $O(n^3)$ ;
- Using rotation trees for a set of segments –  $O(n^2)$ . *M. H. Overmars and E. Welzl, 1988*

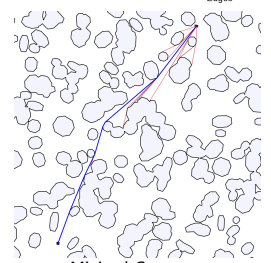


# Minimal Construct: Efficient Shortest Path in Polygonal Maps

- **Minimal Construct** algorithm computes visibility graph during the A\* search instead of first computation of the complete visibility graph and then finding the shortest path using A\* or Dijkstra algorithm.
- Based on A\* search with line intersection tests are delayed until they become necessary.
- The intersection tests are further accelerated using bounding boxes.



Full Visibility Graph



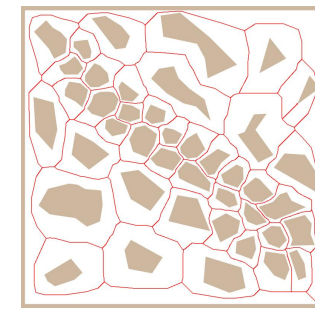
Minimal Construct

Marcell Missura, Daniel D. Lee, and Maren Bennewitz (2018): **Minimal Construct: Efficient Shortest Path Finding for Mobile Robots in Polygonal Maps.** IROS.

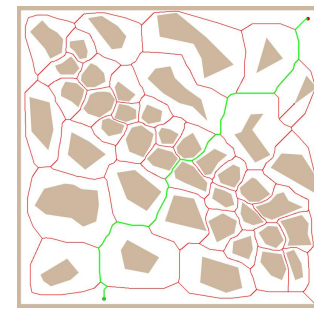


# Voronoi Graph

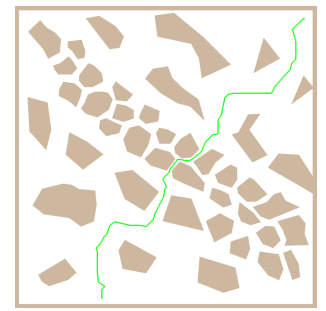
1. Roadmap is Voronoi graph that maximizes clearance from the obstacles.
2. Start and goal positions are connected to the graph.
3. Path is found using a graph search algorithm.



Voronoi graph



Path in graph



Found path

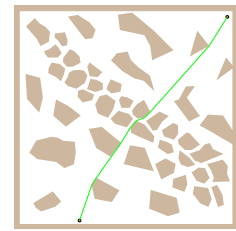


### Visibility Graph vs Voronoi Graph

#### Visibility graph

- Shortest path, but it is close to obstacles. We have to consider safety of the path.
- Complicated in higher dimensions

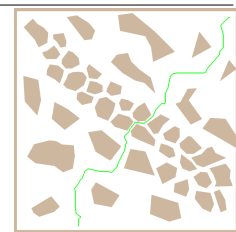
An error in plan execution can lead to a collision.



#### Voronoi graph

- It maximizes clearance, which can provide conservative paths.
- Small changes in obstacles can lead to large changes in the graph.
- Complicated in higher dimensions.

A combination is called Visibility-Voronoi – R. Wein, J. P. van den Berg, D. Halperin, 2004.

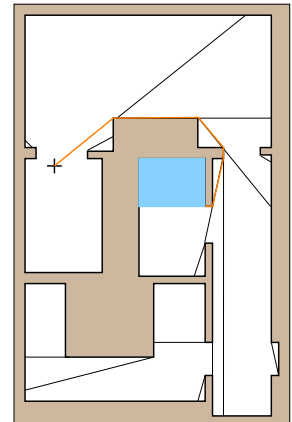


For higher dimensions we need other types of roadmaps.



### Shortest Path Map (SPM)

- Speedup computation of the shortest path towards a particular goal location  $p_g$  for a polygonal domain  $\mathcal{P}$  with  $n$  vertices.
- A partitioning of the free space into cells with respect to the particular location  $p_g$ .
- Each cell has a vertex on the shortest path to  $p_g$ .
- Shortest path from any point  $p$  is found by determining the cell (in  $O(\log n)$  using point location alg.) and then traversing the shortest path with up to  $k$  bends, i.e., it is found in  $O(\log n + k)$ .
- Determining the SPM using “wavefront” propagation based on *continuous Dijkstra paradigm*.
- SPM is a precompute structure for the given  $\mathcal{P}$  and  $p_g$ ;
  - single-point query.

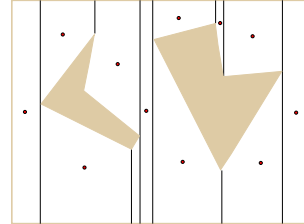


A similar structure can be found for two-point query, e.g., H. Guo, A. Maheshwari, J.-R. Sack, 2008.

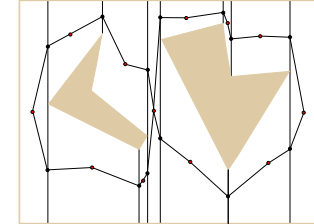
### Cell Decomposition

- Decompose free space into parts. Any two points in a convex region can be directly connected by a segment.
- Create an adjacency graph representing the connectivity of the free space.
- Find a path in the graph.

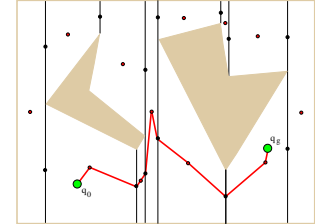
#### Trapezoidal decomposition



Centroids represent cells



Connect adjacency cells



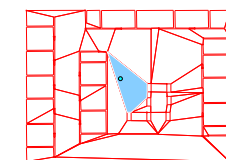
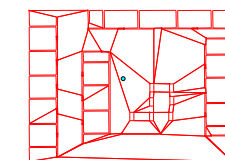
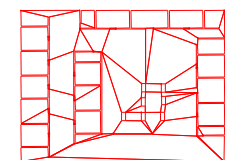
Find path in the adjacency graph

- Other decomposition (e.g., triangulation) are possible.



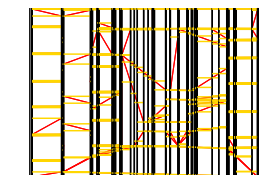
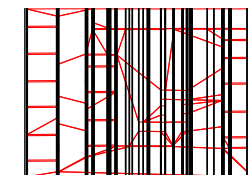
### Point Location Problem

- For a given partitioning of the polygonal domain into a discrete set of cells, determine the cell for a given point  $p$ .



Masato Edahiro, Iwao Kokubo and Takao Asano: A new point-location algorithm and its practical efficiency: comparison with existing algorithms, ACM Trans. Graph., 3(2):86–109, 1984.

- It can be implemented using **interval trees** – slabs and slices.

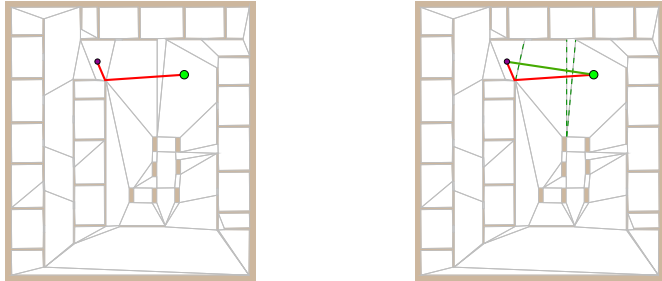


Point location problem, SPM and similarly problems are from the Computational Geometry field.



## Approximate Shortest Path and Navigation Mesh

- We can use any convex partitioning of the polygonal map to speed up shortest path queries.
  1. Precompute all shortest paths from map vertices to  $p_g$  using visibility graph.
  2. Then, an estimation of the shortest path from  $p$  to  $p_g$  is the shortest path among the one of the cell vertex.



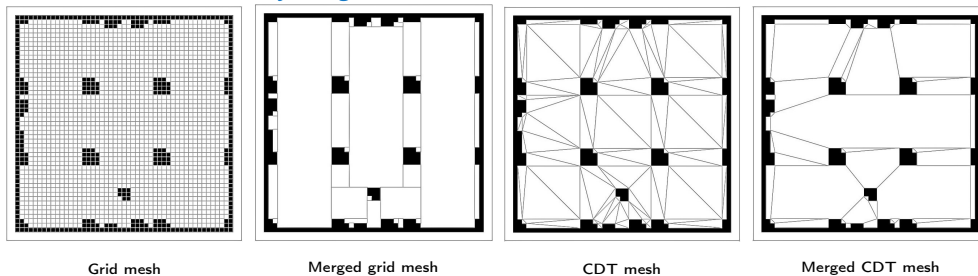
- The estimation can be further improved by “ray-shooting” technique combined with walking in triangulation (convex partitioning). (Faigl, 2010)



## Navigation Mesh

- In addition to robotic approaches, fast shortest path queries are studied in computer games.
- There is a class of algorithms based on navigation mesh.
  - A supporting structure representing the free space.

*It usually originated from the grid based maps, but it is represented as **CDT – Constrained Delaunay triangulation**.*



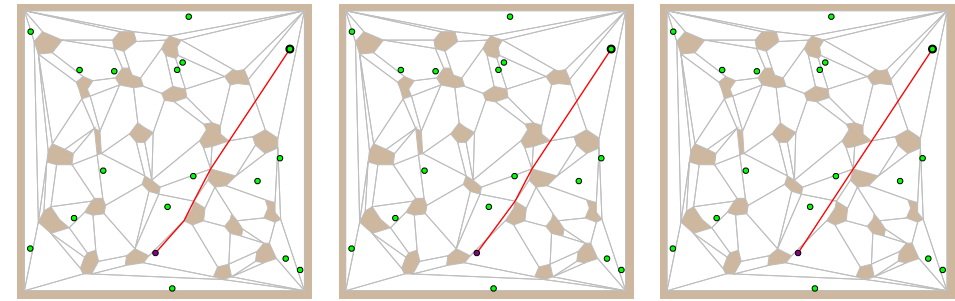
- E.g., **Polyanya** algorithm based on navigation mesh and best-first search.

*M. Cui, D. Harabor, A. Grastien: **Compromise-free Pathfinding on a Navigation Mesh**, IJCAI 2017, 496–502. <https://bitbucket.org/dharabor/pathfinding>*



## Path Refinement

- Testing collision of the point  $p$  with particular vertices of the estimation of the shortest path.
  - Let the initial path estimation from  $p$  to  $p_g$  be a sequence of  $k$  vertices  $(p, v_1, \dots, v_k, p_g)$ .
  - We can iteratively test if the segment  $(p, v_i)$ ,  $1 < i \leq k$  is collision free up to  $(p, p_g)$ .

Path over  $v_0$ Path over  $v_1$ 

Full refinement

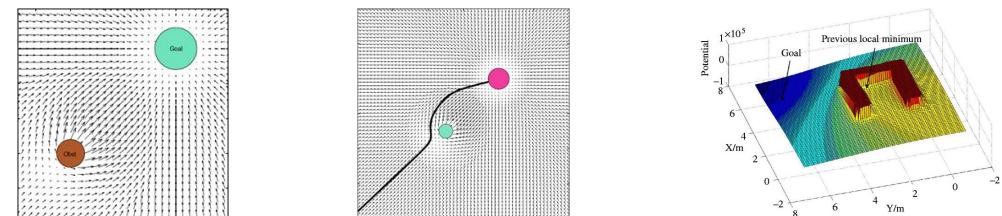
*With the precomputed structures, an estimate of the shortest path is determined in units of microseconds.*



## Artificial Potential Field Method

- The idea is to create a function  $f$  that will provide a direction towards the goal for any configuration of the robot.
- Such a function is called **navigation function** and  $-\nabla f(q)$  points to the goal.
- Create a **potential field** that will **attract robot towards the goal**  $q_f$  while obstacles will generate **repulsive potential** repelling the robot away from the obstacles.

*The navigation function is a sum of potentials.*



*Such a potential function can have several local minima.*

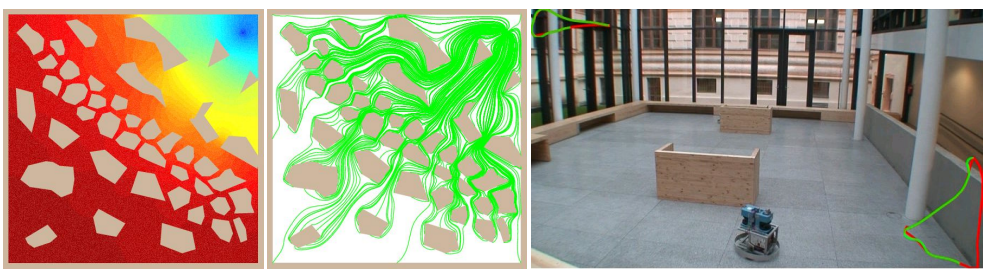


### Avoiding Local Minima in Artificial Potential Field

- Consider harmonic functions that have only one extremum

$$\nabla^2 f(q) = 0.$$

- Finite element method with defined Dirichlet and Neumann boundary conditions.

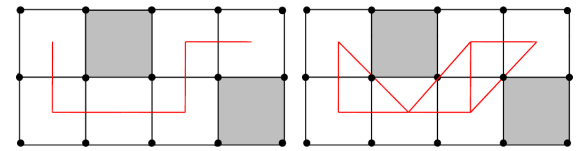


J. Mačák, Master thesis, CTU, 2009

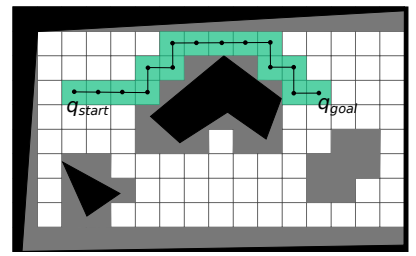
### Grid-based Planning

- A subdivision of  $C_{free}$  into smaller cells.
- Grow obstacles** can be simplified by growing borders by a diameter of the robot.
- Construction of the planning graph  $G = (V, E)$  for  $V$  as a set of cells and  $E$  as the **neighbor-relations**.

- 4-neighbors and 8-neighbors



- A grid map can be constructed from the so-called occupancy grid maps. *E.g., using thresholding.*

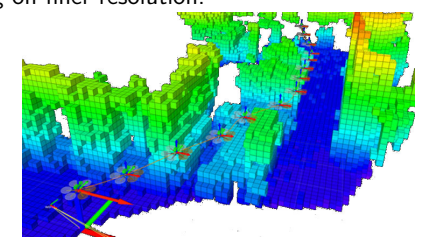
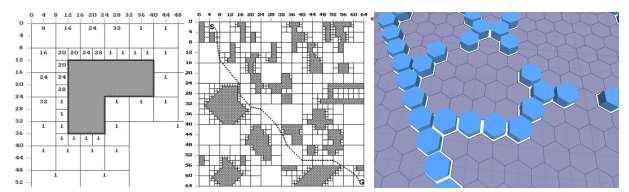


### Part II

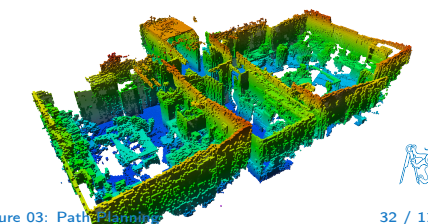
### Part 2 – Grid and Graph based Path Planning Methods

### Grid-based Environment Representations

- Hierarchical planning with coarse resolution and re-planning on finer resolution. Holte, R. C. et al. (1996): Hierarchical A\*: searching abstraction hierarchies efficiently. AAAI.

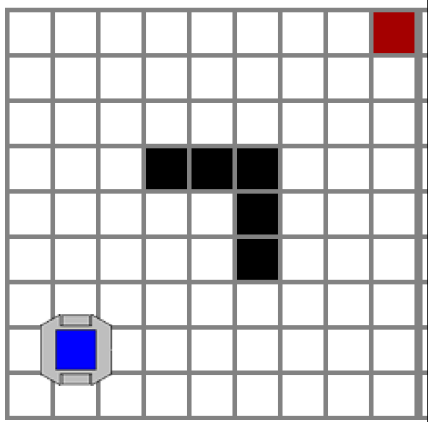


- Octree can be used for the map representation.
- In addition to squared (or rectangular) grid a hexagonal grid can be used.
- 3D grid maps – **OctoMap** <https://octomap.github.io>.
  - Memory grows with the size of the environment.
  - Due to limited resolution it may fail in narrow passages of  $C_{free}$ .

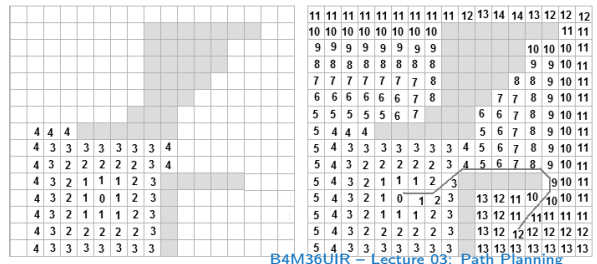
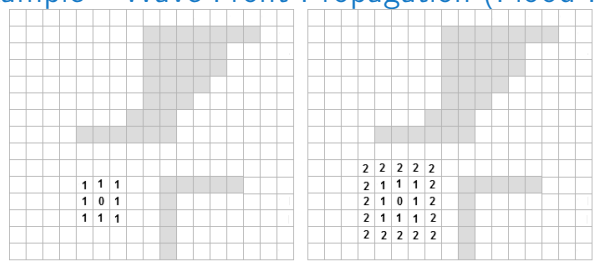


### Example of Simple Grid-based Planning

- Wave-front propagation using path simplification
- Initial map with a robot and goal.
- Obstacle growing.
- Wave-front propagation – “flood fill”.
- Find a path using a navigation function.
- Path simplification.
  - “Ray-shooting” technique combined with **Bresenham’s line algorithm**.
  - The path is a sequence of “key” cells for avoiding obstacles.

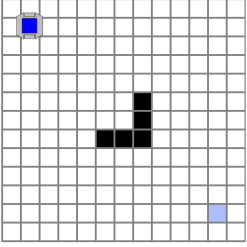


### Example – Wave-Front Propagation (Flood Fill)

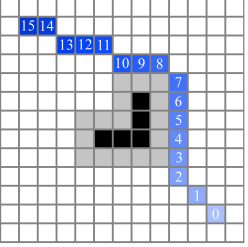


### Path Simplification

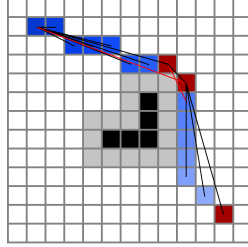
- The initial path is found in a grid using 8-neighborhood.
- The rayshoot cast a line into a grid and possible collisions of the robot with obstacles are checked.
- The “farthest” cells without collisions are used as “turn” points.
- The final path is a sequence of straight line segments.



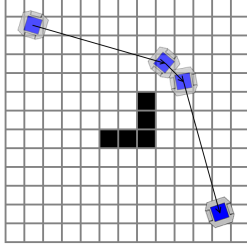
Initial and goal locations



Obstacle growing, wave-front propagation



Ray-shooting



Simplified path

### Bresenham’s Line Algorithm

- Filling a grid by a line with avoiding float numbers.
- A line from  $(x_0, y_0)$  to  $(x_1, y_1)$  is given by  $y = \frac{y_1 - y_0}{x_1 - x_0} (x - x_0) + y_0$ .

```

1 CoordsVector& bresenham(const Coords& pt1, const Coords& pt2,
2   CoordsVector& line)
3 {
4   // The pt2 point is not added into line
5   int x0 = pt1.c; int y0 = pt1.r;
6   int x1 = pt2.c; int y1 = pt2.r;
7   Coords p;
8   int dx = x1 - x0;
9   int dy = y1 - y0;
10  int stepp = (abs(dy) >= abs(dx));
11  if (stepp) {
12    SWAP(x0, y0);
13    SWAP(x1, y1);
14    dx = x1 - x0; // recompute Dx, Dy
15    dy = y1 - y0;
16  }
17  int xstep = 1;
18  if (dx < 0) {
19    xstep = -1;
20    dx = -dx;
21  }
22  int ystep = 1;
23  if (dy < 0) {
24    ystep = -1;
25    dy = -dy;
26  }
27  int twoDy = 2 * dy;
28  int twoDyTwoDx = twoDy - 2 * dx; //2*Dy - 2*Dx
29  int e = twoDy - dx; //2*Dy - Dx
30  int y = y0;
31  for (int x = x0; x != x1; x += xstep) {
32    if (stepp) {
33      xDraw = y;
34      yDraw = x;
35    } else {
36      xDraw = x;
37      yDraw = y;
38    }
39    p.c = xDraw;
40    p.r = yDraw;
41    line.push_back(p); // add to the line
42    if (e > 0) {
43      e += twoDyTwoDx; //E += 2*Dy - 2*Dx
44      y = y + ystep;
45    } else {
46      e += twoDy; //E += 2*Dy
47    }
48  }
49  return line;
50 }
    
```





## Distance Transform based Path Planning

- For a given goal location and grid map compute a navigational function using *wave-front* algorithm, i.e., a kind of *potential field*.
  - The value of the goal cell is set to 0 and all other free cells are set to some very high value.
  - For each free cell compute a number of cells towards the goal cell.
  - It uses 8-neighbors and distance is the Euclidean distance of the centers of two cells, i.e.,  $EV=1$  for orthogonal cells or  $EV = \sqrt{2}$  for diagonal cells.
  - The values are iteratively computed until the values are changing.
  - The value of the cell  $c$  is computed as

$$cost(c) = \min_{i=1}^8 (cost(c_i) + EV_{c_i,c}),$$

where  $c_i$  is one of the neighboring cells from 8-neighborhood of the cell  $c$ .

- The algorithm provides a cost map of the path distance from any free cell to the goal cell.
- The path is then used following the gradient of the cell cost.

Jarvis, R. (2004): Distance Transform Based Visibility Measures for Covert Path Planning in Known but Dynamic Environments.



## Distance Transform based Path Planning – Impl. 1/2

```

1 Grid& DT::compute(Grid& grid) const          35
2 {                                           36
3     static const double DIAGONAL = sqrt(2); 37
4     static const double ORTOGONAL = 1;      38
5     const int H = map.H;                   39
6     const int W = map.W;                   40
7     assert(grid.H == H and grid.W == W, "size"); 41
8     bool anyChange = true;                 42
9     int counter = 0;                        43
10    while (anyChange) {                     44
11        anyChange = false;                  45
12        for (int r = 1; r < H - 1; ++r) {   46
13            for (int c = 1; c < W - 1; ++c) { 47
14                if (map[r][c] != FREESPACE) { 48
15                    continue;                49
16                } //obstacle detected       50
17                double t[4];                 51
18                t[0] = grid[r - 1][c - 1] + DIAGONAL; 52
19                t[1] = grid[r - 1][c] + ORTOGONAL; 53
20                t[2] = grid[r - 1][c + 1] + DIAGONAL; 54
21                t[3] = grid[r][c - 1] + ORTOGONAL; 55
22                double pom = grid[r][c];     56
23                for (int i = 0; i < 4; i++) { 57
24                    if (pom > t[i]) {         58
25                        pom = t[i];           59
26                        anyChange = true;    60
27                    }                         61
28                }                             62
29                if (anyChange) {             63
30                    grid[r][c] = pom;
31                }
32            }
33        }

```

A boundary is assumed around the rectangular map



## Distance Transform Path Planning

### Algorithm 1: Distance Transform for Path Planning

```

for y := 0 to yMax do
    for x := 0 to xMax do
        if goal [x,y] then
            cell [x,y] := 0;
        else
            cell [x,y] := xMax * yMax; //initialization, e.g., pragmatic of the use longest distance as ∞ ;
    repeat
        for y := 1 to (yMax - 1) do
            for x := 1 to (xMax - 1) do
                if not blocked [x,y] then
                    cell [x,y] := cost(x, y);
            for y := (yMax-1) downto 1 do
                for x := (xMax-1) downto 1 do
                    if not blocked [x,y] then
                        cell[x,y] := cost(x, y);
    until no change;

```



## Distance Transform based Path Planning – Impl. 2/2

- The path is retrived by following the minimal value towards the goal using `min8Point()`.

```

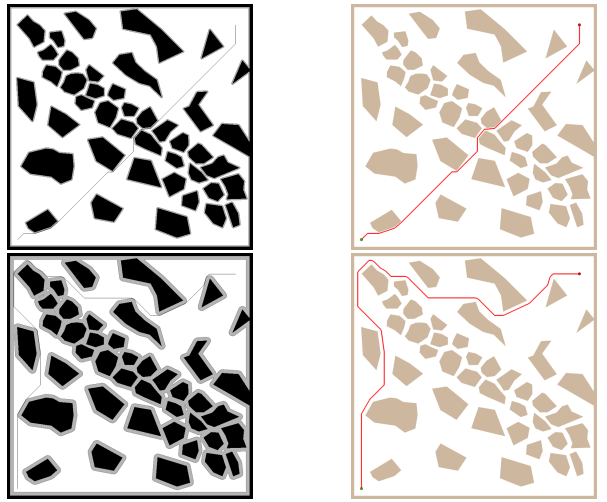
1 Coords& min8Point(const Grid& grid, Coords& p)          22 CoordsVector& DT::findPath(const Coords& start, const Coords&
2 {                                                       goal, CoordsVector& path)
3     double min = std::numeric_limits<double>::max();    23 {
4     const int H = grid.H;                               24     static const double DIAGONAL = sqrt(2);
5     const int W = grid.W;                               25     static const double ORTOGONAL = 1;
6     Coords t;                                           26     const int H = map.H;
7                                                         27     const int W = map.W;
8     for (int r = p.r - 1; r <= p.r + 1; r++) {         28     Grid grid(H, W, H*W); // H*W max grid value
9         if (r < 0 or r >= H) { continue; }             29     grid[goal.r][goal.c] = 0;
10        for (int c = p.c - 1; c <= p.c + 1; c++) {     30     compute(grid);
11            if (c < 0 or c >= W) { continue; }         31
12            if (min > grid[r][c]) {                    32     if (grid[start.r][start.c] >= H*W) {
13                min = grid[r][c];                      33         WARN("Path has not been found");
14                t.r = r; t.c = c;                       34     } else {
15            }                                             35         Coords pt = start;
16        }                                                 36         while (pt.r != goal.r or pt.c != goal.c) {
17    }                                                       37             path.push_back(pt);
18    p = t;                                                 38             min8Point(grid, pt);
19    return p;                                             39     }
20 }                                                       40     path.push_back(goal);
                                                         41     }
                                                         42     return path;
                                                         43 }

```



### DT Example

- $\delta = 10$  cm,  $L = 27.2$  m
- $\delta = 30$  cm,  $L = 42.8$  m



### Graph Search Algorithms

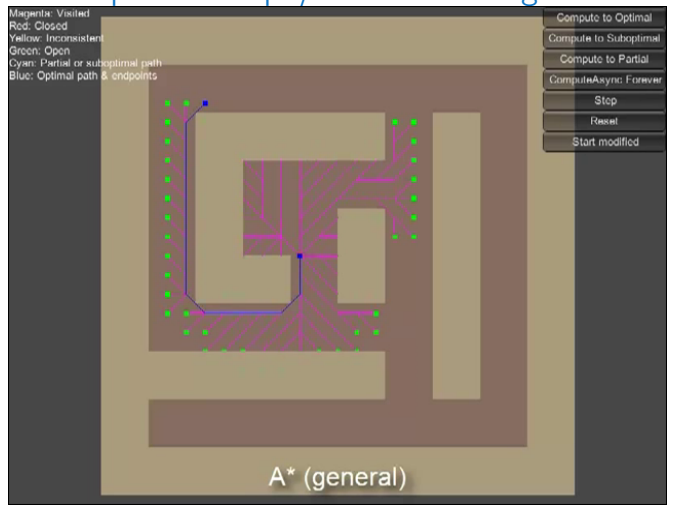
- The grid can be considered as a graph and the path can be found using graph search algorithms.
- The search algorithms working on a graph are of general use, e.g.,
  - Breadth-first search (BFS);
  - Depth first search (DFS);
  - Dijkstra's algorithm;
  - A\* algorithm and its variants.
- There can be grid based speedups techniques, e.g.,
  - **Jump Search Algorithm (JPS)** and **JPS<sup>+</sup>**.
- There are many search algorithms for on-line search, incremental search and with any-time and real-time properties, e.g.,
  - Lifelong Planning A\* (LPA\*).
  - E-Graphs – Experience graphs

Koenig, S., Likhachev, M. and Furcy, D. (2004): Lifelong Planning A\*. AIJ.

Phillips, M. et al. (2012): E-Graphs: Bootstrapping Planning with Experience Graphs. RSS.



### Examples of Graph/Grid Search Algorithms



A\* (general)



### A\* Algorithm

- A\* uses a user-defined  $h$ -values (heuristic) to focus the search.
    - Peter Hart, Nils Nilsson, and Bertram Raphael, 1968
    - Prefer expansion of the node  $n$  with the lowest value
- $$f(n) = g(n) + h(n),$$
- where  $g(n)$  is the cost (path length) from the start to  $n$  and  $h(n)$  is the estimated cost from  $n$  to the goal.
- $h$ -values approximate the goal distance from particular nodes.
  - **Admissibility condition** – heuristic always underestimate the remaining cost to reach the goal.
    - Let  $h^*(n)$  be the true cost of the optimal path from  $n$  to the goal.
    - Then  $h(n)$  is **admissible** if for all  $n$ :  $h(n) \leq h^*(n)$ . *Do we need admissible? When and why?*
    - E.g., Euclidean distance is admissible.
      - A straight line will always be the shortest path.
  - Dijkstra's algorithm –  $h(n) = 0$ .



## A\* Implementation Notes

- The most costly operations of A\* are:
  - Insert and lookup an element in the **closed list**;
  - Insert element and get minimal element (according to  $f()$  value) from the **open list**.
- The **closed list** can be efficiently implemented as a **hash set**.
- The **open list** is usually implemented as a **priority queue**, e.g.,
  - Fibonacci heap, binomial heap,  $k$ -level bucket;
  - binary heap** is usually sufficient with  $O(\log n)$ .
- Forward A\*
  - Create a search tree and initiate it with the start location.
  - Select generated but not yet expanded state  $s$  with the smallest  $f$ -value,  $f(s) = g(s) + h(s)$ .
  - Stop if  $s$  is the goal.
  - Expand the state  $s$ .
  - Goto Step 2.

Similar to Dijkstra's algorithm but it uses  $f(s)$  with the heuristic  $h(s)$  instead of pure  $g(s)$ .

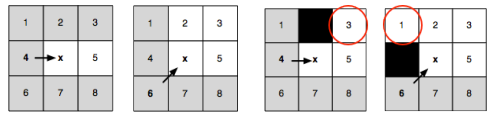


## Jump Point Search Algorithm for Grid-based Path Planning

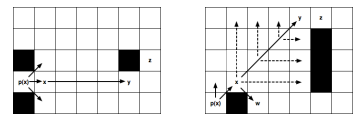
- Jump Point Search (JPS)** algorithm is based on a macro operator that identifies and selectively expands only certain nodes (**jump points**).

Harabor, D. and Grastien, A. (2011): Online Graph Pruning for Pathfinding on Grid Maps. AAAI.

- Natural neighbors after neighbor pruning with forced neighbors because of obstacle.



- Intermediate nodes on a path connecting two jump points are never expanded.



- No preprocessing and no memory overheads while it speeds up A\*.

<https://harablog.wordpress.com/2011/09/07/jump-point-search/>

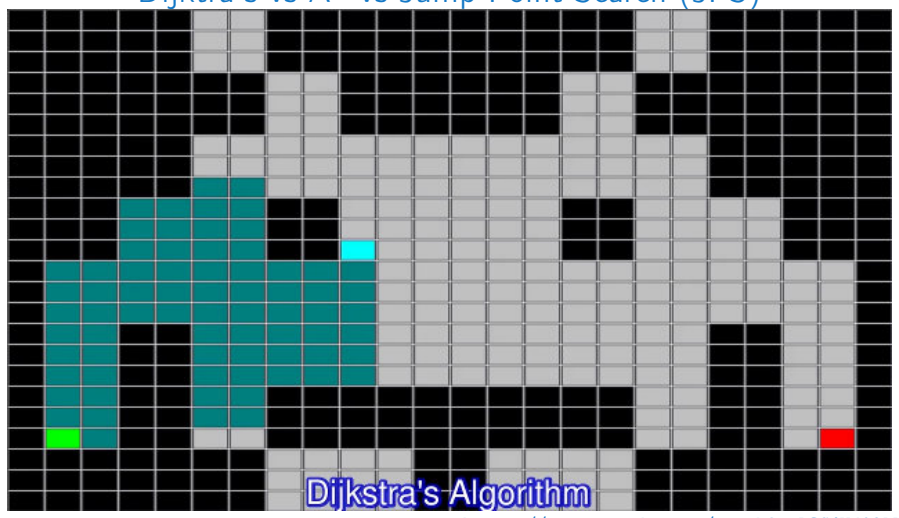
- JPS+ is optimized preprocessed version of JPS with goal bounding.

<https://github.com/SteveRabin/JPSPlusWithGoalBounding>

<http://www.gdcvault.com/play/1022094/JPS-Over-100x-Faster-than>



## Dijkstra's vs A\* vs Jump Point Search (JPS)



## Theta\* – Any-Angle Path Planning Algorithm

- Any-angle path planning algorithms** simplify the path during the search.
- Theta\*** is an extension of A\* with `LineOfSight()`.

Nash, A., Daniel, K, Koenig, S. and Felner, A. (2007): Theta\*: Any-Angle Path Planning on Grids. AAAI.

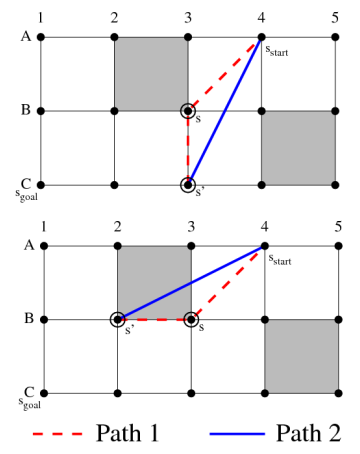
### Algorithm 2: Theta\* Any-Angle Planning

```

if LineOfSight(parent(s), s') then
    /* Path 2 – any-angle path */
    if g(parent(s)) + c(parent(s), s') < g(s') then
        parent(s') := parent(s);
        g(s') := g(parent(s)) + c(parent(s), s');
else
    /* Path 1 – A* path */
    if g(s) + c(s, s') < g(s') then
        parent(s') := s;
        g(s') := g(s) + c(s, s');
    
```

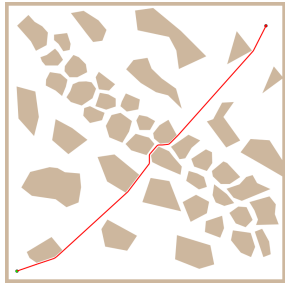
- Path 2: considers path from start to parent(s) and from parent(s) to  $s'$  if  $s'$  has line-of-sight to parent(s).

<http://aigamedev.com/open/tutorials/theta-star-any-angle-paths/>



## Theta\* Any-Angle Path Planning Examples

- Example of found paths by the Theta\* algorithm for the same problems as for the DT-based examples on Slide 42.



$\delta = 10 \text{ cm}, L = 26.3 \text{ m}$



$\delta = 30 \text{ cm}, L = 40.3 \text{ m}$

The same path planning problems solved by DT (without path smoothing) have  $L_{\delta=10} = 27.2 \text{ m}$  and  $L_{\delta=30} = 42.8 \text{ m}$ , while DT seems to be significantly faster.

- Lazy Theta\*** – reduces the number of line-of-sight checks.

Nash, A., Koenig, S. and Tovey, C. (2010): Lazy Theta\*: Any-Angle Path Planning and Path Length Analysis in 3D. AAAI. <http://aigamedev.com/open/tutorial/lazy-theta-star/>



## Real-Time Adaptive A\* (RTAA\*)

- Execute A\* with limited **look-ahead**.
- Learns better informed **heuristic** from the experience, initially  $h(s)$ , e.g., Euclidean distance.
- Look-ahead defines **trade-off** between optimality and computational cost.
  - `astar(lookahead)`

A\* expansion as far as "lookahead" nodes and it terminates with the state  $s'$ .

```

while ( $s_{curr} \notin GOAL$ ) do
  astar(lookahead);
  if  $s' = FAILURE$  then
    return FAILURE;
  for all  $s \in CLOSED$  do
     $H(s) := g(s') + h(s') - g(s)$ ;
    execute(plan); // perform one step
return SUCCESS;
    
```

$s'$  is the last state expanded during the previous A\* search.

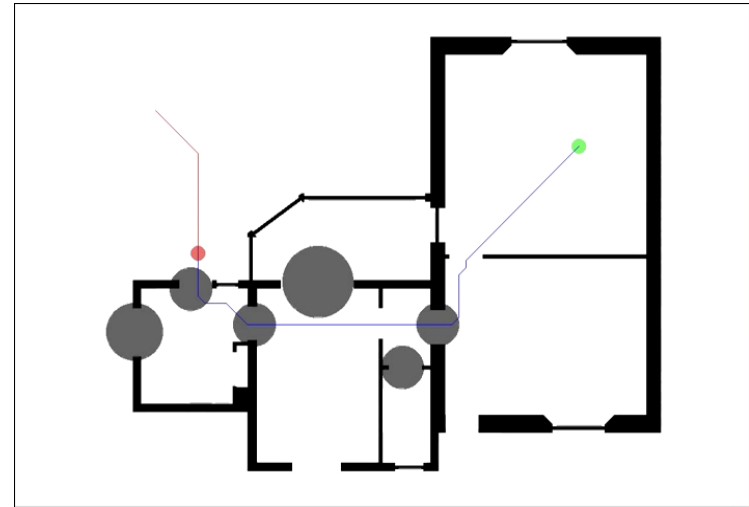


## A\* Variants – Online Search

- The state space (map) may not be known exactly in advance.
  - Environment can **dynamically** change.
  - True travel costs are **experienced** during the path execution.
- Repeated A\* searches can be computationally demanding.
- Incremental heuristic search**
  - Repeated planning of the path from the current state to the goal.
  - Planning under the **free-space** assumption.
  - Reuse** information from the previous searches (**closed list** entries).
    - Focused Dynamic A\* (**D\***) –  $h^*$  is based on **traversability**, it has been used, e.g., for the Mars rover "Opportunity"
      - Stentz, A. (1995): The Focussed D\* Algorithm for Real-Time Replanning. IJCAI.
    - D\* Lite** – similar to D\*
      - Koenig, S. and Likhachev, M. (2005): Fast Replanning for Navigation in Unknown Terrain. T-RO.
- Real-Time Heuristic Search**
  - Repeated planning with limited **look-ahead** – suboptimal but fast
    - Learning Real-Time A\* (**LRTA\***) Korf, E. (1990): Real-time heuristic search. JAI.
    - Real-Time Adaptive A\* (**RTAA\***) Koenig, S. and Likhachev, M. (2006): Real-time adaptive A\*. AAMAS.



## D\* Lite – Demo



## D\* Lite Overview

- It is similar to D\*, but it is based on **Lifelong Planning A\***.
  - Koenig, S. and Likhachev, M. (2002): D\* Lite. AAAI.
- It searches from the goal node to the start node, i.e.,  $g$ -values estimate the goal distance.
- Store pending nodes in a priority queue.
- Process nodes in order of increasing objective function value.
- Incrementally repair solution paths when changes occur.
- Maintains two estimates of costs per node:
  - $g$  – the objective function value – based on what we know;
  - $rhs$  – one-step lookahead of the objective function value – based on what we know.
- Consistency:**
  - Consistent –  $g = rhs$ ;
  - Inconsistent –  $g \neq rhs$ .
- Inconsistent nodes are stored in the priority queue (open list) for processing.



## D\* Lite Algorithm

- Main** – repeat until the robot reaches the goal (or  $g(s_{start}) = \infty$  there is no path).

```
Initialize();
ComputeShortestPath();
while (s_start != s_goal) do
    s_start = argmin_{s' in Succ(s_start)} (c(s_start, s') + g(s'));
    Move to s_start;
    Scan the graph for changed edge costs;
    if any edge cost changed perform then
        foreach directed edges (u, v) with changed edge costs do
            Update the edge cost c(u, v);
            UpdateVertex(u);
        foreach s in U do
            U.Update(s, CalculateKey(s));
    ComputeShortestPath();
```

```
Procedure Initialize
U = 0;
foreach s in S do
    rhs(s) := g(s) := ∞;
rhs(s_goal) := 0;
U.Insert(s_goal, CalculateKey(s_goal));
```

U is priority queue with the vertices.



## D\* Lite: Cost Estimates

- $rhs$  of the node  $u$  is computed based on  $g$  of its successors in the graph and the transition costs of the edge to those successors

$$rhs(u) = \begin{cases} 0 & \text{if } u = s_{start} \\ \min_{s' \in Succ(u)} (g(s') + c(s', u)) & \text{otherwise} \end{cases}$$

- The key/priority of a node  $s$  on the open list is the minimum of  $g(s)$  and  $rhs(s)$  plus a focusing heuristic  $h$

$$[\min(g(s), rhs(s)) + h(s_{start}, s); \min(g(s), rhs(s))].$$

- The first term is used as the primary key.
- The second term is used as the secondary key for tie-breaking.



## D\* Lite Algorithm – ComputeShortestPath()

### Procedure ComputeShortestPath

```
while U.TopKey() < CalculateKey(s_start) OR rhs(s_start) != g(s_start) do
    u := U.Pop();
    if g(u) > rhs(u) then
        g(u) := rhs(u);
        foreach s in Pred(u) do UpdateVertex(s);
    else
        g(u) := ∞;
        foreach s in Pred(u) ∪ {u} do UpdateVertex(s);
```

### Procedure UpdateVertex

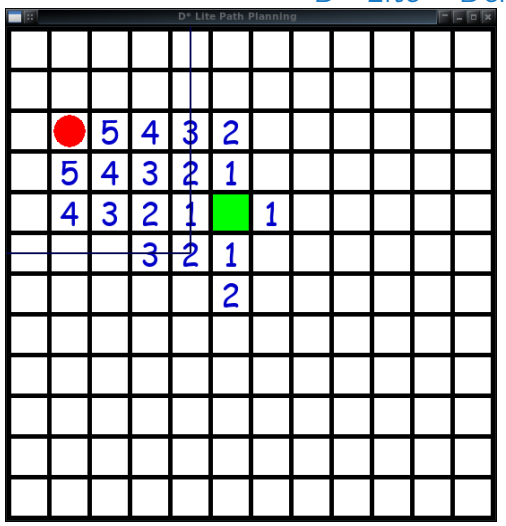
```
if u != s_goal then rhs(u) := min_{s' in Succ(u)} (c(u, s') + g(s'));
if u in U then U.Remove(u);
if g(u) != rhs(u) then U.Insert(u, CalculateKey(u));
```

### Procedure CalculateKey

```
return [min(g(s), rhs(s)) + h(s_start, s); min(g(s), rhs(s))]
```

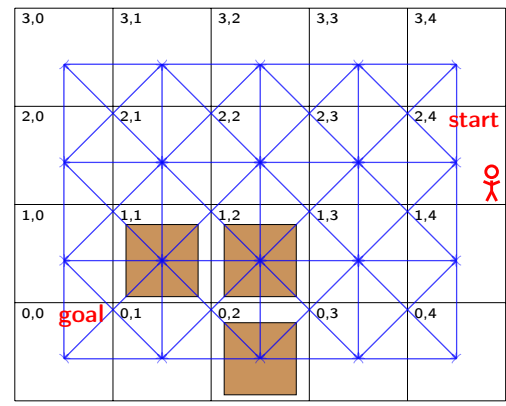


### D\* Lite – Demo



<https://github.com/mdeyo/d-star-lite>

### D\* Lite – Example



**Legend**

- Free node
- Obstacle node
- On open list
- Active node

- A grid map of the environment (what is actually known).
- 8-connected graph superimposed on the grid (bidirectional).
- Focusing heuristic is not used ( $h = 0$ ).

- Transition costs
  - Free space – Free space: 1.0 and 1.4 (for diagonal edge).
  - From/to obstacle:  $\infty$ .

### D\* Lite – Example Planning (1)

3,0	3,1	3,2	3,3	3,4
g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$
2,0	2,1	2,2	2,3	2,4 <b>start</b>
g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$
1,0	1,1	1,2	1,3	1,4
g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$
0,0 <b>goal</b>	0,1	0,2	0,3	0,4
g: $\infty$ rhs: 0	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$

**Legend**

- Free node
- Obstacle node
- On open list
- Active node

- Initialization**
- Set  $rhs = 0$  for the goal.
  - Set  $rhs = g = \infty$  for all other nodes.

### D\* Lite – Example Planning (2)

3,0	3,1	3,2	3,3	3,4
g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$
2,0	2,1	2,2	2,3	2,4 <b>start</b>
g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$
1,0	1,1	1,2	1,3	1,4
g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$
0,0 <b>goal</b>	0,1	0,2	0,3	0,4
g: $\infty$ rhs: 0	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$	g: $\infty$ rhs: $\infty$

**Legend**

- Free node
- Obstacle node
- On open list
- Active node

- Initialization**
- Put the goal to the open list.  
It is inconsistent.

### D\* Lite – Example Planning (3–init)

3,0	3,1	3,2	3,3	3,4
g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞
2,0	2,1	2,2	2,3	2,4 <b>start</b>
g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞
1,0	1,1	1,2	1,3	1,4
g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞
0,0 <b>goal</b>	0,1	0,2	0,3	0,4
g: ∞ rhs: 0	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞

- Legend**
- Free node
  - Obstacle node
  - On open list
  - Active node
- ComputeShortestPath**
- Pop the minimum element from the open list (goal).
  - It is over-consistent ( $g > rhs$ ).



### D\* Lite – Example Planning (4)

3,0	3,1	3,2	3,3	3,4
g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞
2,0	2,1	2,2	2,3	2,4 <b>start</b>
g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞
1,0	1,1	1,2	1,3	1,4
g: ∞ rhs: 1	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞
0,0 <b>goal</b>	0,1	0,2	0,3	0,4
g: 0 rhs: 0	g: ∞ rhs: 1	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞

- Legend**
- Free node
  - Obstacle node
  - On open list
  - Active node
- ComputeShortestPath**
- Expand popped node (UpdateVertex()) on all its predecessors.
  - This computes the rhs values for the predecessors.
  - Nodes that become inconsistent are added to the open list.

Small black arrows denote the node used for computing the rhs value, i.e., using the respective transition cost.

- The rhs value of (1,1) is ∞ because the transition to obstacle has cost ∞.



### D\* Lite – Example Planning (3)

3,0	3,1	3,2	3,3	3,4
g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞
2,0	2,1	2,2	2,3	2,4 <b>start</b>
g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞
1,0	1,1	1,2	1,3	1,4
g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞
0,0 <b>goal</b>	0,1	0,2	0,3	0,4
g: 0 rhs: 0	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞

- Legend**
- Free node
  - Obstacle node
  - On open list
  - Active node
- ComputeShortestPath**
- Pop the minimum element from the open list (goal).
  - It is over-consistent ( $g > rhs$ ) therefore set  $g = rhs$ .



### D\* Lite – Example Planning (5–init)

3,0	3,1	3,2	3,3	3,4
g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞
2,0	2,1	2,2	2,3	2,4 <b>start</b>
g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞
1,0	1,1	1,2	1,3	1,4
g: ∞ rhs: 1	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞
0,0 <b>goal</b>	0,1	0,2	0,3	0,4
g: 0 rhs: 0	g: ∞ rhs: 1	g: ∞ rhs: ∞	g: ∞ rhs: ∞	g: ∞ rhs: ∞

- Legend**
- Free node
  - Obstacle node
  - On open list
  - Active node
- ComputeShortestPath**
- Pop the minimum element from the open list (1,0).
  - It is over-consistent ( $g > rhs$ ).



### D\* Lite – Example Planning (5)

3,0 g: ∞ rhs: ∞	3,1 g: ∞ rhs: ∞	3,2 g: ∞ rhs: ∞	3,3 g: ∞ rhs: ∞	3,4 g: ∞ rhs: ∞
2,0 g: ∞ rhs: ∞	2,1 g: ∞ rhs: ∞	2,2 g: ∞ rhs: ∞	2,3 g: ∞ rhs: ∞	2,4 <b>start</b> g: ∞ rhs: ∞
1,0 g: 1 rhs: 1	1,1 g: ∞ rhs: ∞	1,2 g: ∞ rhs: ∞	1,3 g: ∞ rhs: ∞	1,4 g: ∞ rhs: ∞
0,0 <b>goal</b> g: 0 rhs: 0	0,1 g: ∞ rhs: 1	0,2 g: ∞ rhs: ∞	0,3 g: ∞ rhs: ∞	0,4 g: ∞ rhs: ∞

**Legend**

Free node (white)    Obstacle node (brown)

On open list (green)    Active node (pink)

- ComputeShortestPath**
- Pop the minimum element from the open list (1,0).
  - It is over-consistent ( $g > rhs$ ) set  $g = rhs$ .



### D\* Lite – Example Planning (6)

3,0 g: ∞ rhs: ∞	3,1 g: ∞ rhs: ∞	3,2 g: ∞ rhs: ∞	3,3 g: ∞ rhs: ∞	3,4 g: ∞ rhs: ∞
2,0 g: ∞ rhs: 2	2,1 g: ∞ rhs: 2.4	2,2 g: ∞ rhs: ∞	2,3 g: ∞ rhs: ∞	2,4 <b>start</b> g: ∞ rhs: ∞
1,0 g: 1 rhs: 1	1,1 g: ∞ rhs: ∞	1,2 g: ∞ rhs: ∞	1,3 g: ∞ rhs: ∞	1,4 g: ∞ rhs: ∞
0,0 <b>goal</b> g: 0 rhs: 0	0,1 g: ∞ rhs: 1	0,2 g: ∞ rhs: ∞	0,3 g: ∞ rhs: ∞	0,4 g: ∞ rhs: ∞

**Legend**

Free node (white)    Obstacle node (brown)

On open list (green)    Active node (pink)

- ComputeShortestPath**
- Expand the popped node (UpdateVertex() on all predecessors in the graph).
  - Compute rhs values of the predecessors accordingly.
  - Put them to the open list if they become inconsistent.

- The rhs value of (0,0), (1,1) does not change.
- They do not become inconsistent and thus they are not put on the open list.



### D\* Lite – Example Planning (7)

3,0 g: ∞ rhs: ∞	3,1 g: ∞ rhs: ∞	3,2 g: ∞ rhs: ∞	3,3 g: ∞ rhs: ∞	3,4 g: ∞ rhs: ∞
2,0 g: ∞ rhs: 2	2,1 g: ∞ rhs: 2.4	2,2 g: ∞ rhs: ∞	2,3 g: ∞ rhs: ∞	2,4 <b>start</b> g: ∞ rhs: ∞
1,0 g: 1 rhs: 1	1,1 g: ∞ rhs: ∞	1,2 g: ∞ rhs: ∞	1,3 g: ∞ rhs: ∞	1,4 g: ∞ rhs: ∞
0,0 <b>goal</b> g: 0 rhs: 0	0,1 g: 1 rhs: 1	0,2 g: ∞ rhs: ∞	0,3 g: ∞ rhs: ∞	0,4 g: ∞ rhs: ∞

**Legend**

Free node (white)    Obstacle node (brown)

On open list (green)    Active node (pink)

- ComputeShortestPath**
- Pop the minimum element from the open list (0,1).
  - It is over-consistent ( $g > rhs$ ) and thus set  $g = rhs$ .
  - Expand the popped element, e.g., call UpdateVertex().



### D\* Lite – Example Planning (8)

3,0 g: ∞ rhs: ∞	3,1 g: ∞ rhs: ∞	3,2 g: ∞ rhs: ∞	3,3 g: ∞ rhs: ∞	3,4 g: ∞ rhs: ∞
2,0 g: 2 rhs: 2	2,1 g: ∞ rhs: 2.4	2,2 g: ∞ rhs: ∞	2,3 g: ∞ rhs: ∞	2,4 <b>start</b> g: ∞ rhs: ∞
1,0 g: 1 rhs: 1	1,1 g: ∞ rhs: ∞	1,2 g: ∞ rhs: ∞	1,3 g: ∞ rhs: ∞	1,4 g: ∞ rhs: ∞
0,0 <b>goal</b> g: 0 rhs: 0	0,1 g: 1 rhs: 1	0,2 g: ∞ rhs: ∞	0,3 g: ∞ rhs: ∞	0,4 g: ∞ rhs: ∞

**Legend**

Free node (white)    Obstacle node (brown)

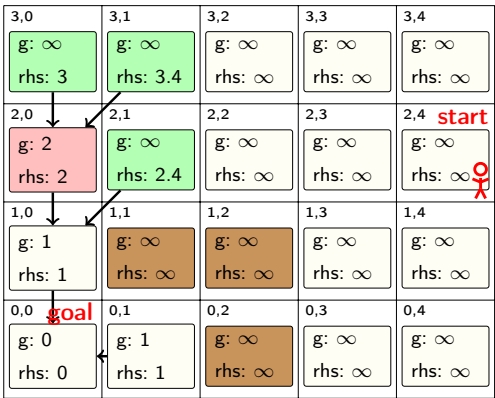
On open list (green)    Active node (pink)

- ComputeShortestPath**
- Pop the minimum element from the open list (2,0).
  - It is over-consistent ( $g > rhs$ ) and thus set  $g = rhs$ .





### D\* Lite – Example Planning (9)



**Legend**

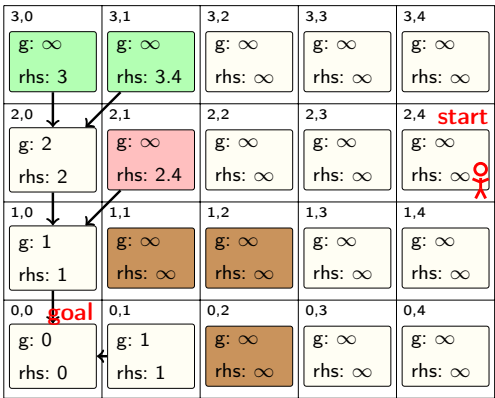
- Free node
- Obstacle node
- On open list
- Active node

**ComputeShortestPath**

- Expand the popped element and put the predecessors that become inconsistent onto the open list.



### D\* Lite – Example Planning (10-init)



**Legend**

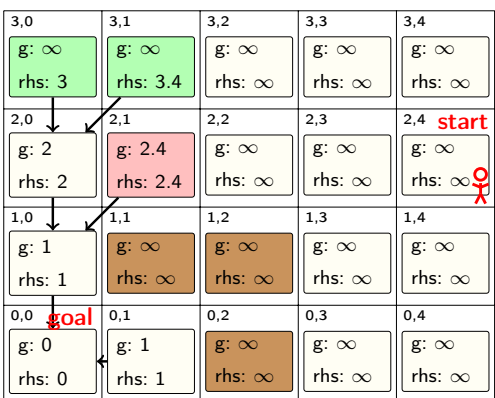
- Free node
- Obstacle node
- On open list
- Active node

**ComputeShortestPath**

- Pop the minimum element from the open list (2,1).
- It is over-consistent ( $g > rhs$ ).



### D\* Lite – Example Planning (10)



**Legend**

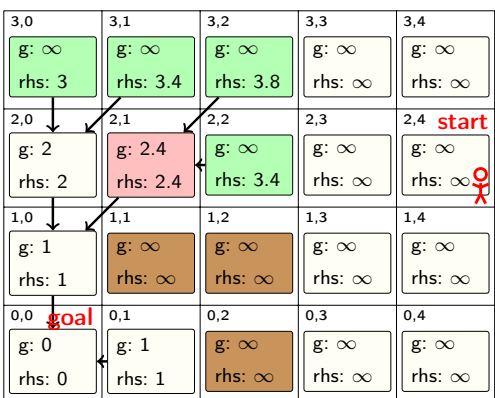
- Free node
- Obstacle node
- On open list
- Active node

**ComputeShortestPath**

- Pop the minimum element from the open list (2,1).
- It is over-consistent ( $g > rhs$ ) and thus set  $g = rhs$ .



### D\* Lite – Example Planning (11)



**Legend**

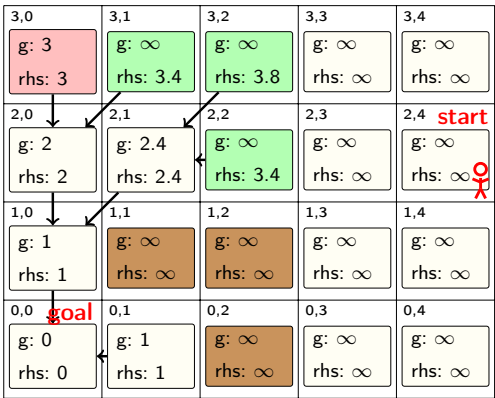
- Free node
- Obstacle node
- On open list
- Active node

**ComputeShortestPath**

- Expand the popped element and put the predecessors that become inconsistent onto the open list.



### D\* Lite – Example Planning (12)



**Legend**

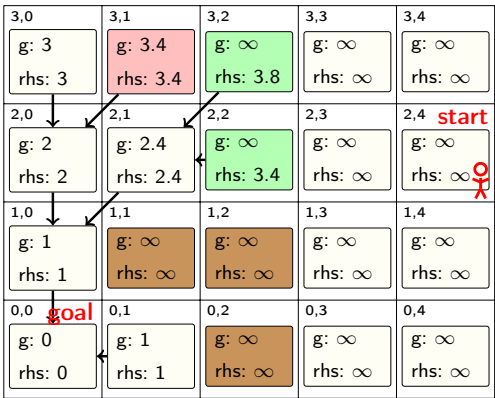
- Free node
- Obstacle node
- On open list
- Active node

**ComputeShortestPath**

- Pop the minimum element from the open list (3,0).
- It is over-consistent ( $g > rhs$ ) and thus set  $g = rhs$ .
- Expand the popped element and put the predecessors that become inconsistent onto the open list.
- In this cases, none of the predecessors become inconsistent.



### D\* Lite – Example Planning (13)



**Legend**

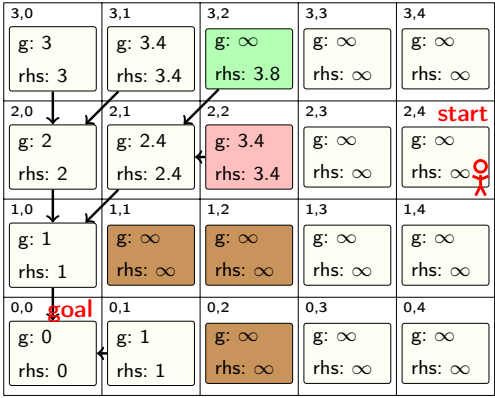
- Free node
- Obstacle node
- On open list
- Active node

**ComputeShortestPath**

- Pop the minimum element from the open list (3,0).
- It is over-consistent ( $g > rhs$ ) and thus set  $g = rhs$ .
- Expand the popped element and put the predecessors that become inconsistent onto the open list.
- In this cases, none of the predecessors become inconsistent.



### D\* Lite – Example Planning (14)



**Legend**

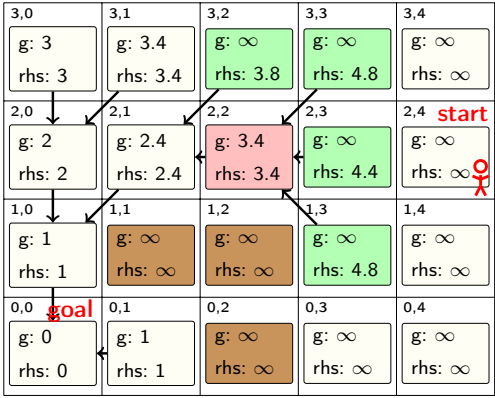
- Free node
- Obstacle node
- On open list
- Active node

**ComputeShortestPath**

- Pop the minimum element from the open list (2,2).
- It is over-consistent ( $g > rhs$ ) and thus set  $g = rhs$ .



### D\* Lite – Example Planning (15)



**Legend**

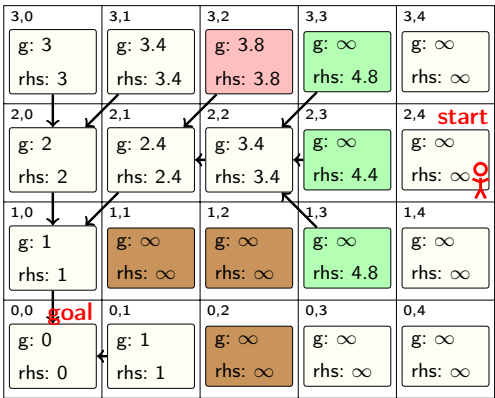
- Free node
- Obstacle node
- On open list
- Active node

**ComputeShortestPath**

- Expand the popped element and put the predecessors that become inconsistent onto the open list, i.e., (3,2), (3,3), (2,3).



### D\* Lite – Example Planning (16)



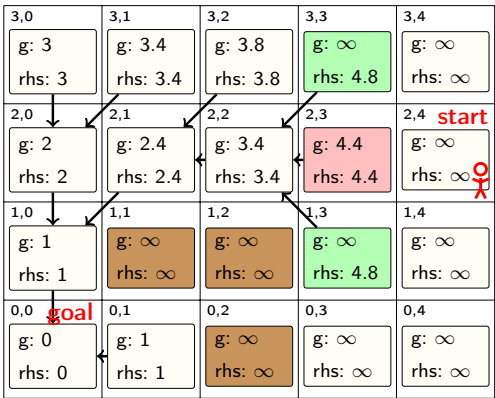
**Legend**

- Free node
- Obstacle node
- On open list
- Active node

- ComputeShortestPath**
- Pop the minimum element from the open list (3,2).
  - It is over-consistent ( $g > rhs$ ) and thus set  $g = rhs$ .
  - Expand the popped element and put the predecessors that become inconsistent onto the open list.
  - In this cases, none of the predecessors become inconsistent.



### D\* Lite – Example Planning (17)



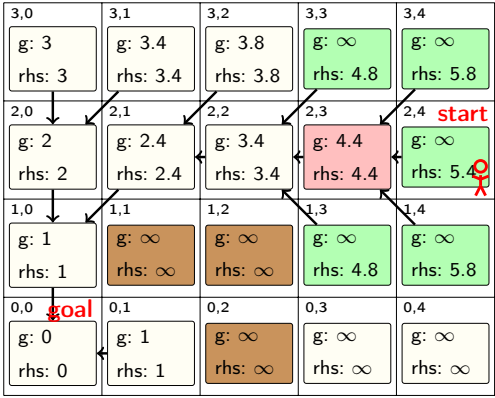
**Legend**

- Free node
- Obstacle node
- On open list
- Active node

- ComputeShortestPath**
- Pop the minimum element from the open list (2,3).
  - It is over-consistent ( $g > rhs$ ) and thus set  $g = rhs$ .



### D\* Lite – Example Planning (18)



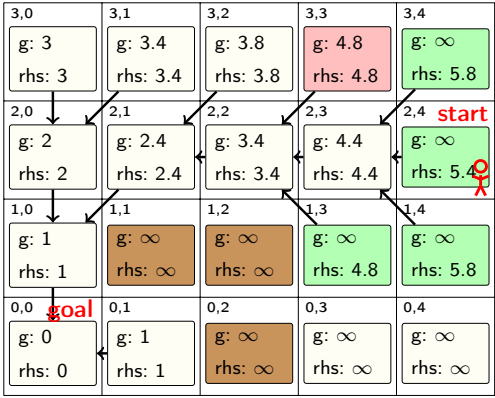
**Legend**

- Free node
- Obstacle node
- On open list
- Active node

- ComputeShortestPath**
- Expand the popped element and put the predecessors that become inconsistent onto the open list, i.e., (3,4), (2,4), (1,4).
  - The start node is on the open list.
  - However, the search does not finish at this stage.
  - There are still inconsistent nodes (on the open list) with a lower value of  $rhs$ .



### D\* Lite – Example Planning (19)



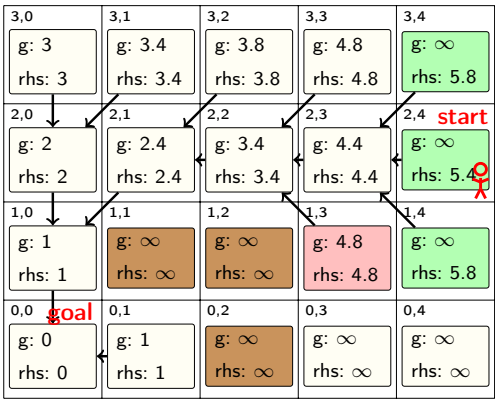
**Legend**

- Free node
- Obstacle node
- On open list
- Active node

- ComputeShortestPath**
- Pop the minimum element from the open list (3,2).
  - It is over-consistent ( $g > rhs$ ) and thus set  $g = rhs$ .
  - Expand the popped element and put the predecessors that become inconsistent onto the open list.
  - In this cases, none of the predecessors become inconsistent.



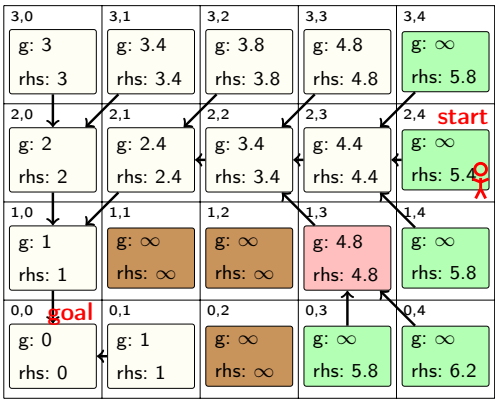
### D\* Lite – Example Planning (20)



- Legend**
- Free node
  - Obstacle node
  - On open list
  - Active node
- ComputeShortestPath**
- Pop the minimum element from the open list (1,3).
  - It is over-consistent ( $g > rhs$ ) and thus set  $g = rhs$ .



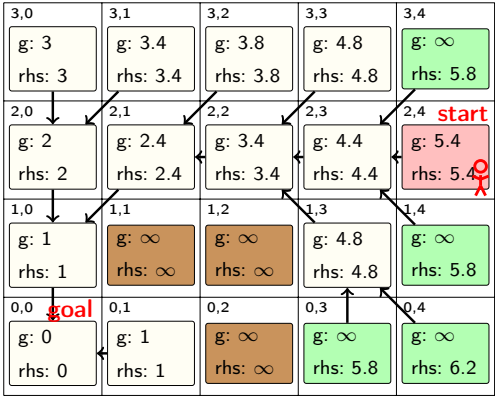
### D\* Lite – Example Planning (21)



- Legend**
- Free node
  - Obstacle node
  - On open list
  - Active node
- ComputeShortestPath**
- Expand the popped element and put the predecessors that become inconsistent onto the open list, i.e., (0,3) and (0,4).



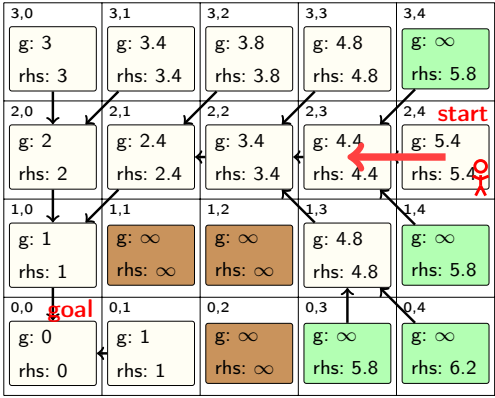
### D\* Lite – Example Planning (22)



- Legend**
- Free node
  - Obstacle node
  - On open list
  - Active node
- ComputeShortestPath**
- Pop the minimum element from the open list (2,4).
  - It is over-consistent ( $g > rhs$ ) and thus set  $g = rhs$ .
  - Expand the popped element and put the predecessors that become inconsistent (none in this case) onto the open list.



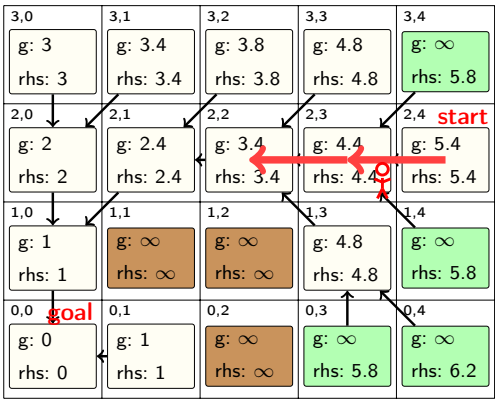
### D\* Lite – Example Planning (23)



- Legend**
- Free node
  - Obstacle node
  - On open list
  - Active node
- Follow the gradient of  $g$  values from the start node.



### D\* Lite – Example Planning (24)



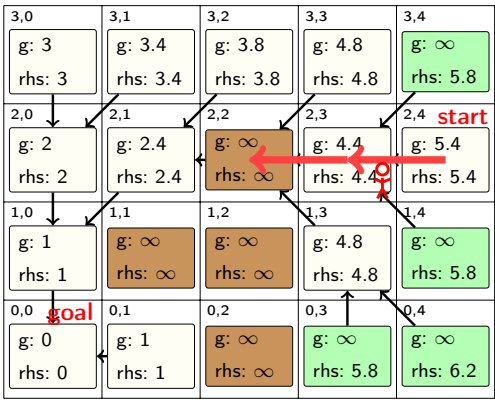
**Legend**

- Free node (white)
- Obstacle node (brown)
- On open list (green)
- Active node (pink)

- Follow the gradient of  $g$  values from the start node.



### D\* Lite – Example Planning (25)



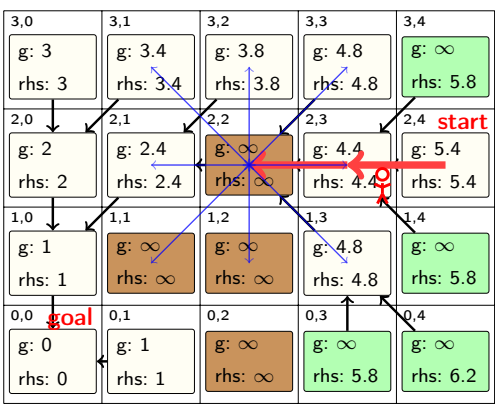
**Legend**

- Free node (white)
- Obstacle node (brown)
- On open list (green)
- Active node (pink)

- A new obstacle is detected during the movement from (2,3) to (2,2).
- Replanning is needed!



### D\* Lite – Example Planning (25 update)



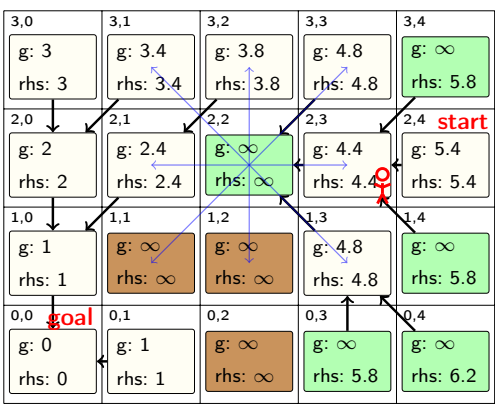
**Legend**

- Free node (white)
- Obstacle node (brown)
- On open list (green)
- Active node (pink)

- All directed edges with changed edge, we need to call the `UpdateVertex()`.
- All edges into and out of (2,2) have to be considered.



### D\* Lite – Example Planning (26 update 1/2)



**Legend**

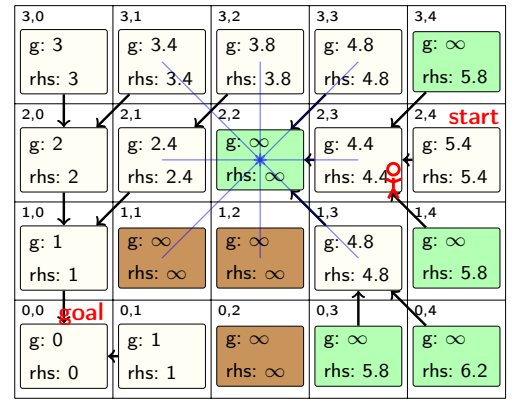
- Free node (white)
- Obstacle node (brown)
- On open list (green)
- Active node (pink)

**Update Vertex**

- Outgoing edges from (2,2).
- Call `UpdateVertex()` on (2,2).
- The transition costs are now  $\infty$  because of obstacle.
- Therefore the  $rhs = \infty$  and (2,2) becomes inconsistent and it is put on the open list.



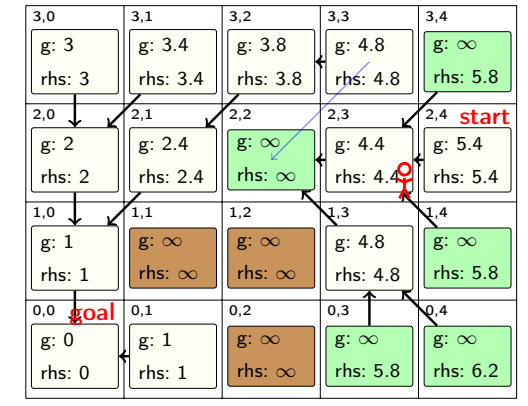
### D\* Lite – Example Planning (26 update 2/2)



- Legend**
- Free node
  - Obstacle node
  - On open list
  - Active node
- Update Vertex**
- Incomming edges to (2,2).
  - Call UpdateVertex() on the neighbors (2,2).
  - The transition cost is ∞, and therefore, the rhs value previously computed using (2,2) is changed.



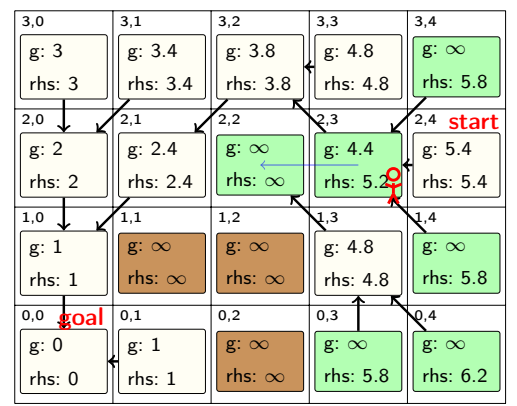
### D\* Lite – Example Planning (27)



- Legend**
- Free node
  - Obstacle node
  - On open list
  - Active node
- Update Vertex**
- The neighbor of (2,2) is (3,3).
  - The minimum possible rhs value of (3,3) is 4.8 but it is based on the g value of (3,2) and not (2,2), which is the detected obstacle.
  - The node (3,3) is still consistent and thus it is not put on the open list.



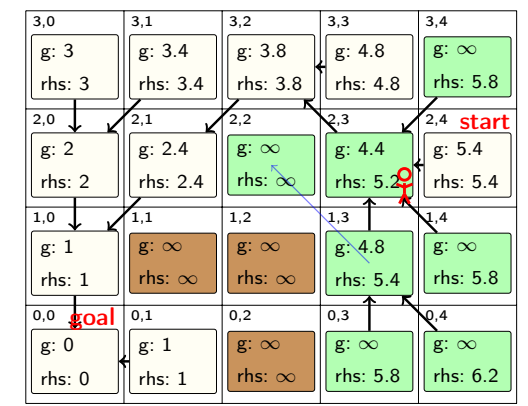
### D\* Lite – Example Planning (28)



- Legend**
- Free node
  - Obstacle node
  - On open list
  - Active node
- Update Vertex**
- (2,3) is also a neighbor of (2,2).
  - The minimum possible rhs value of (2,3) is 5.2 because (2,2) is an obstacle (using (3,2) with 3.8 + 1.4).
  - The rhs value of (2,3) is different from g; thus, (2,3) is put on the open list.



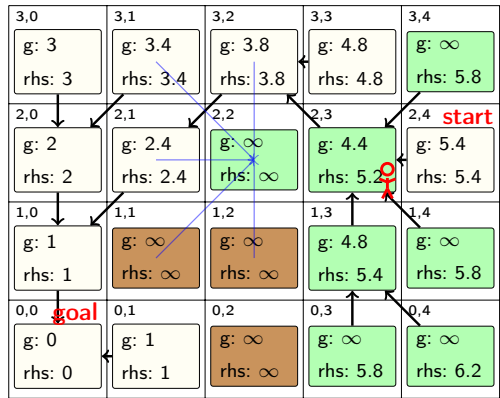
### D\* Lite – Example Planning (29)



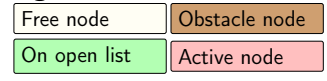
- Legend**
- Free node
  - Obstacle node
  - On open list
  - Active node
- Update Vertex**
- Another neighbor of (2,2) is (1,3).
  - The minimum possible rhs value of (1,3) is 5.4 computed based on g of (2,3) with 4.4 + 1 = 5.4.
  - The rhs value is always computed using the g values of its successors.



### D\* Lite – Example Planning (29 update)



#### Legend



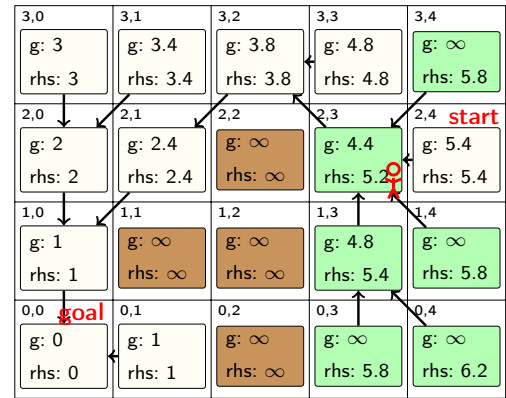
#### Update Vertex

- None of the other neighbor of (2,2) end up being inconsistent.
- We go back to calling ComputeShortestPath() until an optimal path is determined.

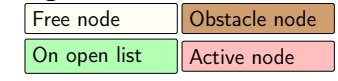
- The node corresponding to the robot's current position is inconsistent and its key is greater than the minimum key on the open list.
- Thus, the optimal path is not found yet.



### D\* Lite – Example Planning (30)



#### Legend



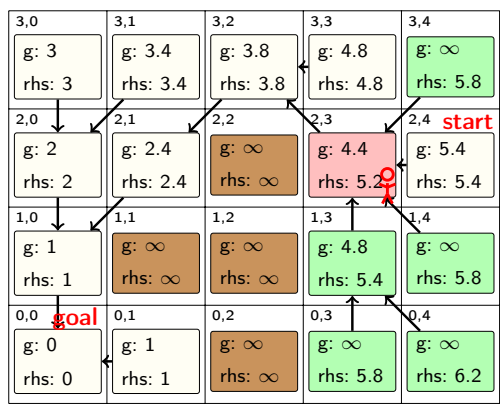
#### ComputeShortestPath

- Pop the minimum element from the open list (2,2), which is obstacle.
- It is under-consistent ( $g < rhs$ ), therefore set  $g = \infty$ .
- Expand the popped element and put the predecessors that become inconsistent (none in this case) onto the open list.

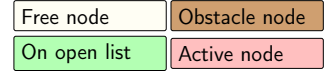
- Because (2,2) was under-consistent (when popped), UpdateVertex() has to be called on it.
- However, it has no effect as its rhs value is up to date and consistent.



### D\* Lite – Example Planning (31-init)



#### Legend



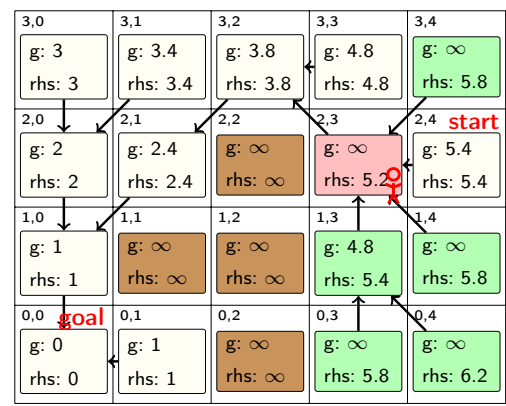
#### ComputeShortestPath

- Pop the minimum element from the open list (2,3).
- It is under-consistent  $g < rhs$ .

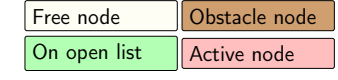
- The node corresponding to the robot's current position is inconsistent and its key is greater than the minimum key on the open list.
- Thus, the optimal path is not found yet.



### D\* Lite – Example Planning (31)



#### Legend



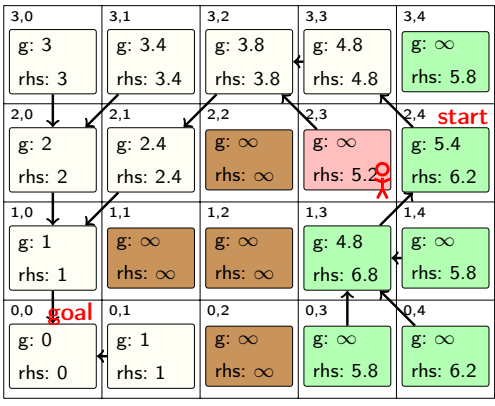
#### ComputeShortestPath

- Pop the minimum element from the open list (2,3).
- It is under-consistent  $g < rhs$  therefore set  $g = \infty$ .

- The node corresponding to the robot's current position is inconsistent and its key is greater than the minimum key on the open list.
- Thus, the optimal path is not found yet.



### D\* Lite – Example Planning (32)



**Legend**

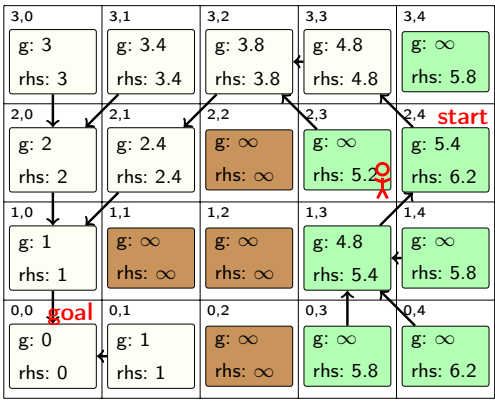
- Free node
- Obstacle node
- On open list
- Active node

**ComputeShortestPath**

- Expand the popped element and update the predecessors.
- (2,4) becomes inconsistent.
- (1,3) gets updated and still inconsistent.
- The rhs value (1,4) does not change, but it is now computed from the g value of (1,3).



### D\* Lite – Example Planning (33)



**Legend**

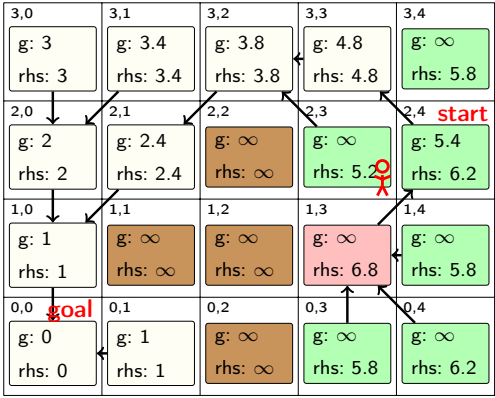
- Free node
- Obstacle node
- On open list
- Active node

**ComputeShortestPath**

- Because (2,3) was under-consistent (when popped), a call `UpdateVertex()` on it is needed.
- As it is still inconsistent it is put back onto the open list.



### D\* Lite – Example Planning (34)



**Legend**

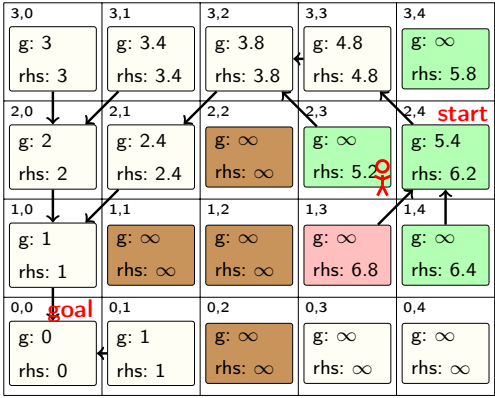
- Free node
- Obstacle node
- On open list
- Active node

**ComputeShortestPath**

- Pop the minimum element from the open list (1,3).
- It is under-consistent ( $g < rhs$ ), therefore set  $g = \infty$ .



### D\* Lite – Example Planning (35)



**Legend**

- Free node
- Obstacle node
- On open list
- Active node

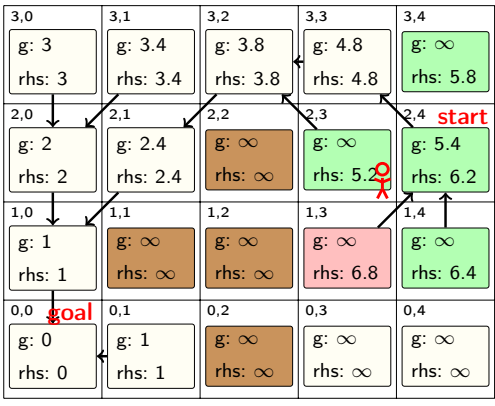
**ComputeShortestPath**

- Expand the popped element and update the predecessors.
- (1,4) gets updated and still inconsistent.
- (0,3) and (0,4) get updated and now consistent (both g and rhs are ∞).





### D\* Lite – Example Planning (36)



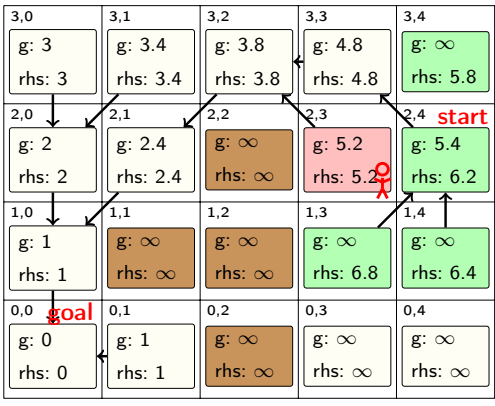
**Legend**

- Free node
- Obstacle node
- On open list
- Active node

- ComputeShortestPath**
- Because (1,3) was under-consistent (when popped), call UpdateVertex() on it is needed.
  - As it is still inconsistent it is put back onto the open list.



### D\* Lite – Example Planning (37)



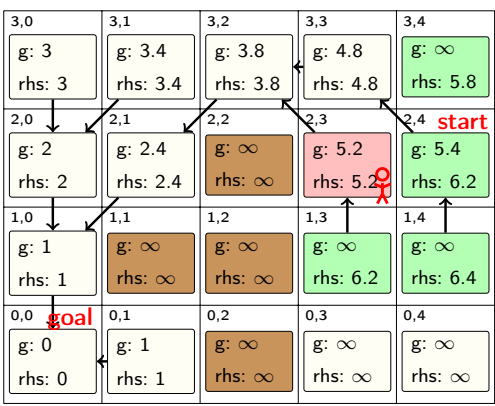
**Legend**

- Free node
- Obstacle node
- On open list
- Active node

- ComputeShortestPath**
- Pop the minimum element from the open list (2,3).
  - It is over-consistent ( $g > rhs$ ), therefore set  $g = rhs$ .



### D\* Lite – Example Planning (38)



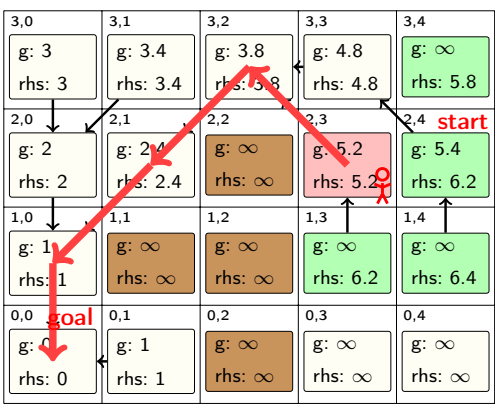
**Legend**

- Free node
- Obstacle node
- On open list
- Active node

- ComputeShortestPath**
- Expand the popped element and update the predecessors.
  - (1,3) gets updated and still inconsistent.
  - The node (2,3) corresponding to the robot's position is consistent.
  - Besides, the top of the key on the open list is not less than the key of (2,3).
  - The optimal path has been found and we can break out of the loop.



### D\* Lite – Example Planning (39)



**Legend**

- Free node
- Obstacle node
- On open list
- Active node

- Follow the gradient of  $g$  values from the robot's current position (node).



## D\* Lite – Comments

- D\* Lite works with real valued costs, not only with binary costs (free/obstacle).
- The search can be focused with an admissible heuristic that would be added to  $g$  and  $rhs$ .
- The final version of D\* Lite includes further optimization (not shown in the example).
  - Updating the  $rhs$  value without considering all successors every time.
  - Re-focusing the search as the robot moves without reordering the entire open list.



## Reaction-Diffusion Background

- FitzHugh-Nagumo (FHN) model *FitzHugh R, Biophysical Journal (1961)*

$$\begin{aligned} \dot{u} &= \varepsilon(u - u^3 - v + \phi) + D_u \Delta u \\ \dot{v} &= (u - \alpha v + \beta) + D_v \Delta u \end{aligned}$$

where  $\alpha, \beta, \varepsilon$ , and  $\phi$  are parameters of the model.

- Dynamics of RD system is determined by the associated *nullcline configurations* for  $\dot{u}=0$  and  $\dot{v}=0$  in the absence of diffusion, i.e.,

$$\begin{aligned} \varepsilon(u - u^3 - v + \phi) &= 0, \\ (u - \alpha v + \beta) &= 0, \end{aligned}$$

which have associated geometrical shapes.



## Reaction-Diffusion Processes Background

- *Reaction-Diffusion* (RD) models – dynamical systems capable to reproduce the autowaves.
- *Autowaves* - a class of nonlinear waves that propagate through an active media.
  - At the expense of the energy stored in the medium, e.g., grass combustion.*
- RD model describes spatio-temporal evolution of two state variables  $u = u(\vec{x}, t)$  and  $v = v(\vec{x}, t)$  in space  $\vec{x}$  and time  $t$

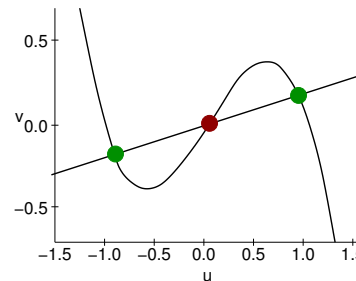
$$\begin{aligned} \dot{u} &= f(u, v) + D_u \Delta u \\ \dot{v} &= g(u, v) + D_v \Delta v \end{aligned}$$

where  $\Delta$  is the Laplacian.

This RD-based path planning is informative, just for *curiosity*.



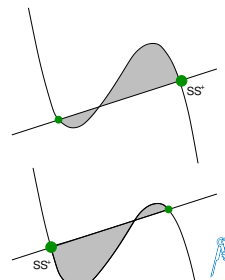
## Nullcline Configurations and Steady States



- Nullclines intersections represent:
  - **Stable States (SSs)**;
  - **Unstable States**.
- Bistable regime

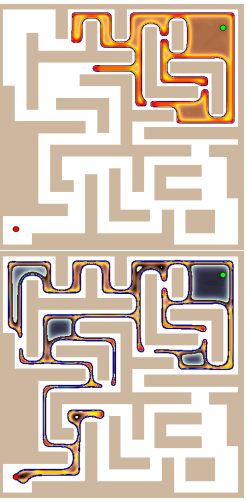
*The system (concentration levels of (u, v) for each grid cell) tends to be in SSs.*

- We can modulate relative stability of both SS.
  - “preference” of SS<sup>+</sup> over SS<sup>-</sup>.*
- System moves from SS<sup>-</sup> to SS<sup>+</sup>, if a small perturbation is introduced.
- The SSs are separated by a mobile frontier – a kind of traveling frontwave (autowaves).

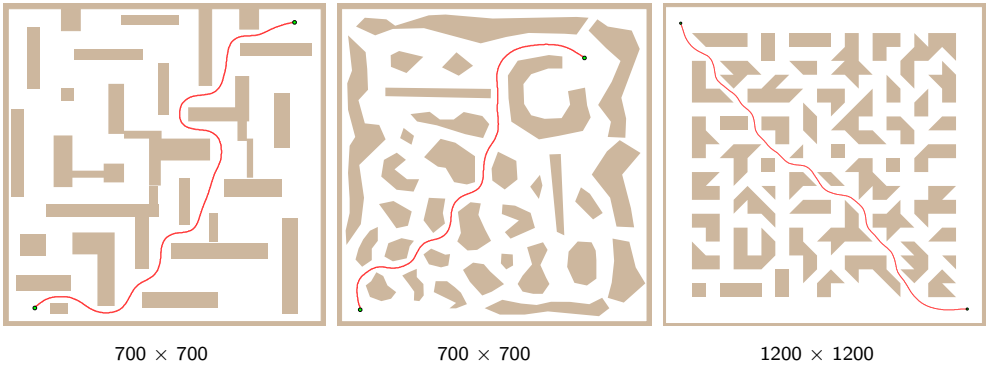


### RD-based Path Planning – Computational Model

- Finite difference method on a Cartesian grid with Dirichlet boundary conditions (FTCS). *discretization → grid based computation → grid map*
- External forcing** – introducing additional information *i.e., constraining concentration levels to some specific values.*
- Two-phase evolution of the underlying RD model.
  - Propagation phase**
    - Freespace is set to  $SS^-$  and the start location  $SS^+$ .
    - Parallel propagation of the frontwave with *non-annihilation property*.  
Vázquez-Otero and Muñuzuri, CNNA (2010)
    - Terminate when the frontwave reaches the goal.
  - Contraction phase**
    - Different nullclines configuration.
    - Start and goal positions are forced towards  $SS^+$ .
    - $SS^-$  shrinks until only the path linking the forced points remains.

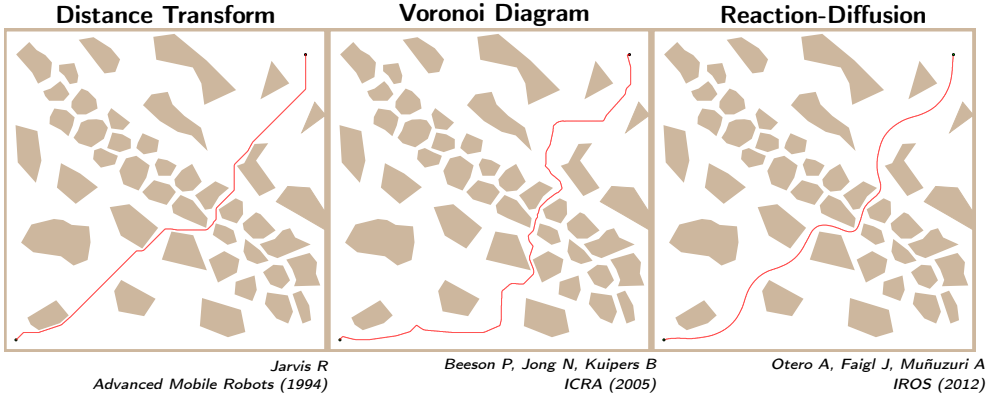


### Example of Found Paths



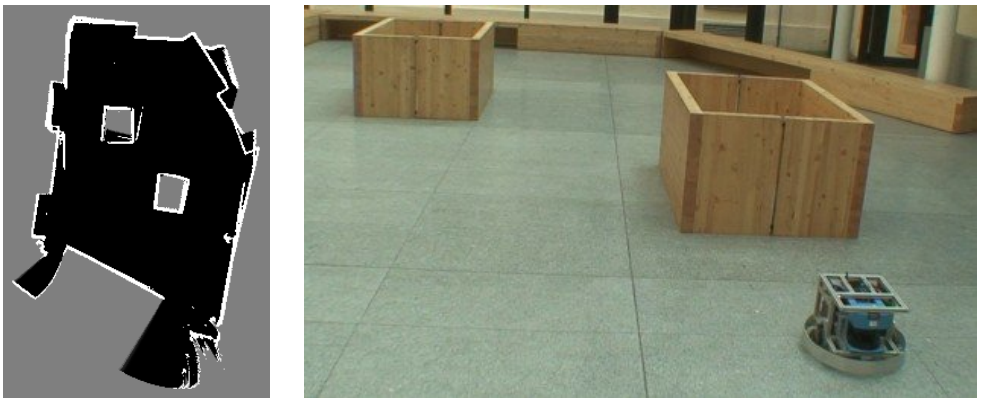
- The path clearance may be adjusted by the **wavelength** and size of the computational grid. *Control of the path distance from the obstacles (path safety).*

### Comparison with Standard Approaches



- RD-based approach provides competitive paths regarding path length and clearance, while they seem to be smooth.

### Robustness to Noisy Data



Vázquez-Otero, A., Faigl, J., Duro, N. and Dormido, R. (2014): Reaction-Diffusion based Computational Model for Autonomous Mobile Robot Exploration of Unknown Environments. International Journal of Unconventional Computing (IJUC).

## Summary of the Lecture



## Topics Discussed

- Motion and path planning problems
  - Path planning methods – overview
  - Notation of configuration space
- Path planning methods for geometrical map representation
  - Shortest-Path Roadmaps
  - Voronoi diagram based planning
  - Cell decomposition method
- Distance transform can be utilized for kind of *navigational function*
  - Front-Wave propagation and path simplification
- Artificial potential field method
- Graph search (planning) methods for grid-like representation
  - Dijkstra's, A\*, JPS, Theta\*
  - Dedicated speed up techniques can be employed to decreasing computational burden, e.g., JPS
  - Grid-path can be smoothed, e.g., using path simplification or Theta\* like algorithms
- We can avoid demanding planning from scratch reusing the previous plan for the updated environment map, e.g., using **D\* Lite**
- Unconventional reaction-diffusion based planning (*informative*)
- **Next: Robotic Information Gathering – Mobile Robot Exploration**

