Artificial Intelligence in Robotics

Lecture 12: Visibility-based pursuit evasion

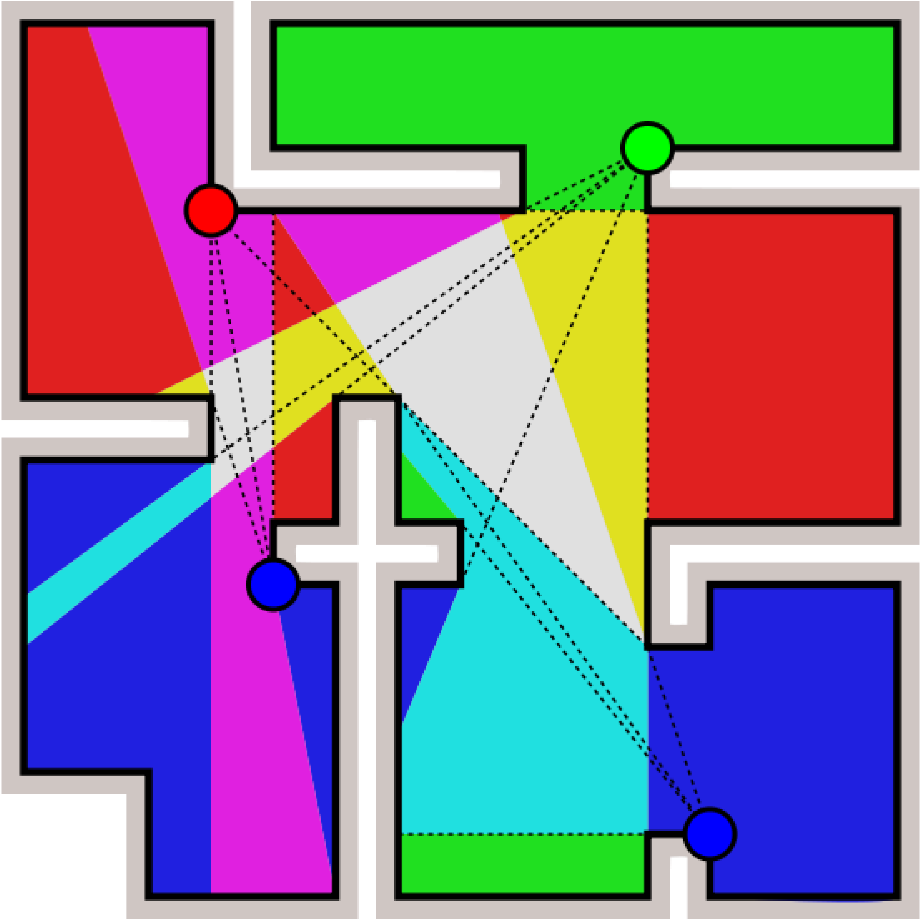
Viliam Lisý

Artificial Intelligence Center
Department of Computer Science, Faculty of Electrical Eng.
Czech Technical University in Prague

Art gallery problem

By Victor Klee in 1973

- simple polygon $\mathrm{P}: v_1, \ldots v_n$
- $x \in P$ covers $y \in P$ iff $xy \subseteq P$
- minimal number of "guards" to cover the whole space?



Picture by Claudio Rocchini

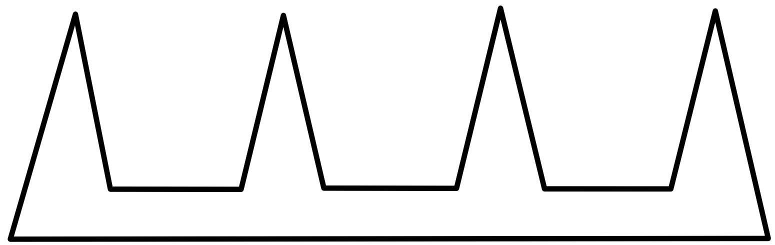
Art gallery problem

Theorem (Václav Chvátal 1975):

$\lfloor n/3 \rfloor$ guard is sometimes necessary and always sufficient to solve the art gallery problem.

Necessary

comb



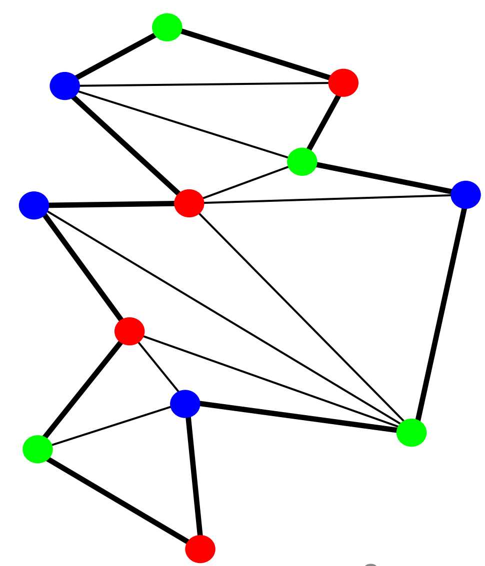
Sufficient (Fisk 1978)

simple polygons always have triangulation

triangulated polygon can be 3-colored

least used color is used no more than $\lfloor n/3 \rfloor$ times

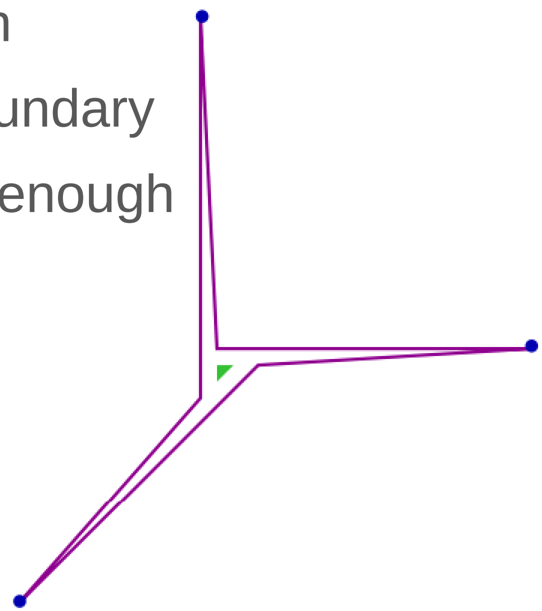
vertices of each color cover the whole polygon

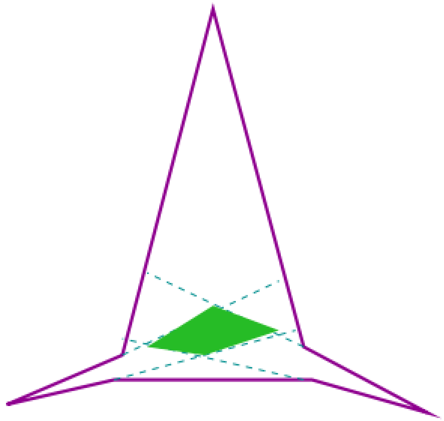


Art gallery problem

Pathological cases (from Subhash Suri's slides):

- less guards may be enough
- optimal positions not on boundary
- seeing the boundary is not enough





Fun facts:

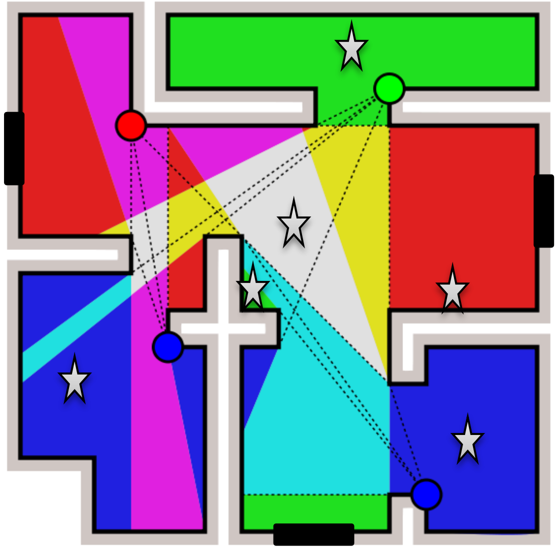
- For orthogonal polygons, only $\lfloor n/4 \rfloor$ guards are needed.
- Computing minimal number of guards for a polygon is NP-hard.
- The problem is closely connected to the set cover problem.

More realistic art gallery problem

There are m cameras (angles)

A guard can watch k cameras

What cameras to show?



Thief has to enter, steal, exit

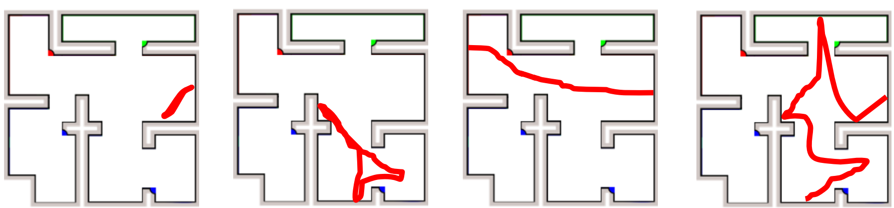
Penalty for each seen second/meter

Inspired by: McMahan, Gordon, Blum: Planning in the presence of cost functions controlled by an adversary. ICML 2003.

Matrix game representation

Defender’s action: watch *k* of *m* cameras

Attacker’s action: path door-target-door



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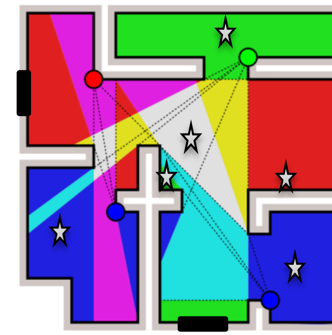
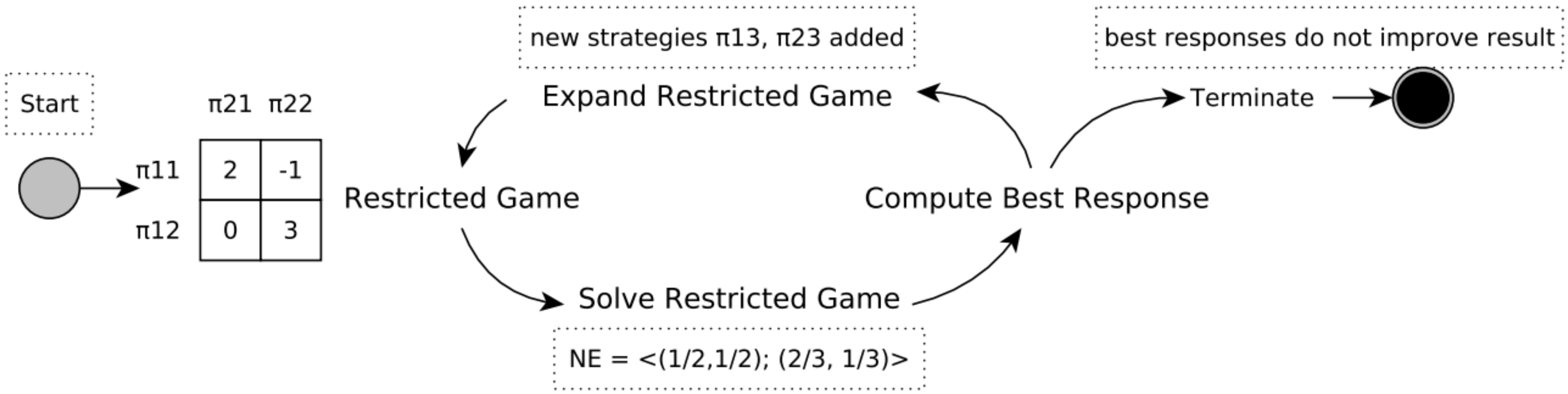


p – prob. of not being detected when seen

$\binom{n}{k}$

$p^{d_1} * v_1$	$v_2 + v_3$	…	…
v_1	$p^{d_2} * (v_2 + v_3)$	…	…
v_1	$v_2 + v_3$	…	…
v_1	$p^{d_3} * (v_2 + v_3)$	…	…

Double oracle framework



McMahan, Gordon, Blum: Planning in the presence of cost functions controlled by an adversary. ICML 2003.

Double-oracle in Matrix game

1	2	4	3	3
	3	3	7	2
	2	4	5	5
	2	1	4	1

Double-oracle in Matrix game

	1			
0	2	4	3	3
1	3	3	7	2
	2	4	5	5
	2	1	4	1

Double-oracle in Matrix game

	0.5			0.5
0.5	2	4	3	3
0.5	3	3	7	2
	2	4	5	5
	2	1	4	1

Double-oracle in Matrix game

	0.75			0.25
0	2	4	3	3
0.75	3	3	7	2
0.25	2	4	5	5
	2	1	4	1

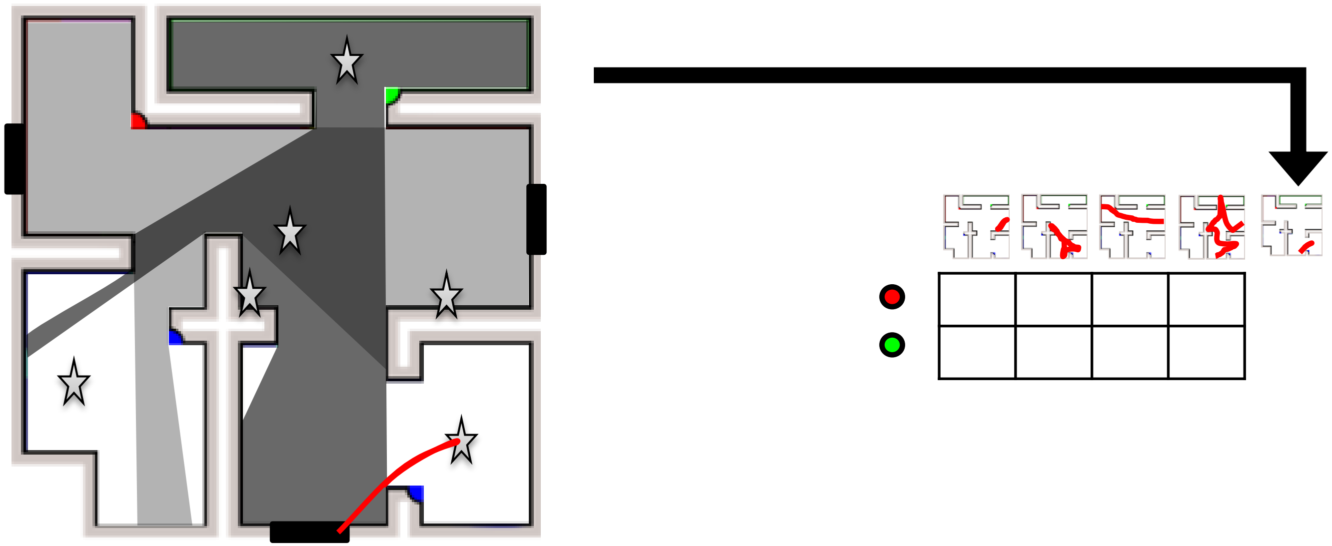
Always converges and finds NE.

Attacker’s best response oracle

Defender’s current strategy

$\frac{1}{3}$

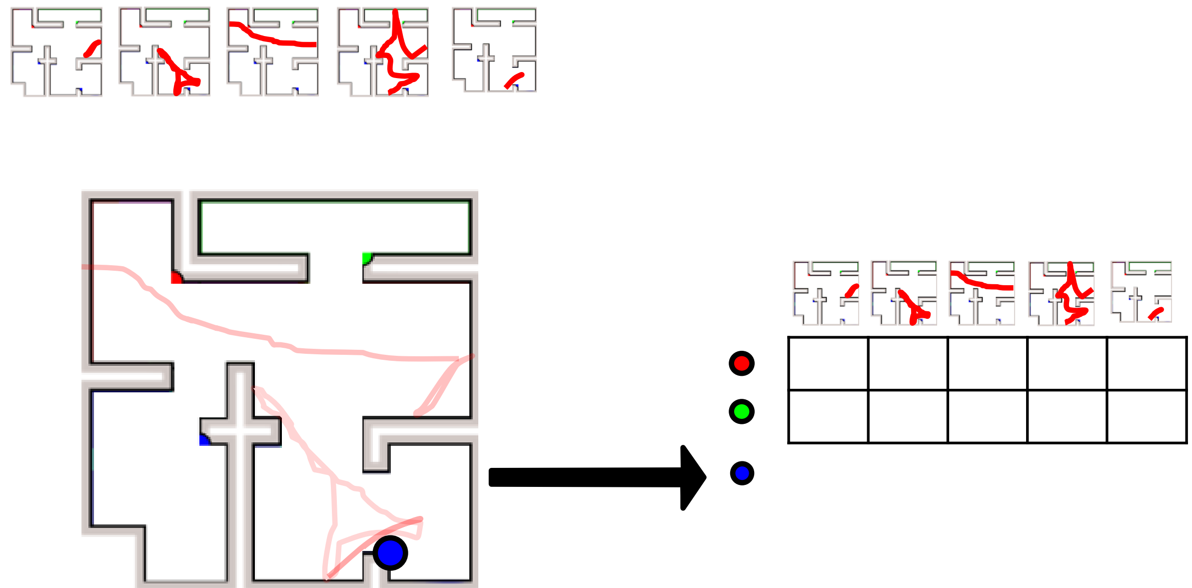
$\frac{2}{3}$



Path planning with costs defined by cameras in use (A*, TSP, etc.)

Defender’s best response oracle

$$\frac{1}{4} \quad \frac{1}{6} \quad \frac{1}{4} \quad 0 \quad \frac{1}{3}$$



Greedy / combinatorial search for best k camera positions

Clearing polygonal environment

Hunters and pray problem

- simple polygon $\mathrm{P}: v_1, \ldots v_n$
- k hunters with bounded speed
- pray with unbounded speed
- can hunters spot the pray?

Definitions

- $h^i: [0, \infty) \rightarrow P$ is the pursuer i's strategy
- $e: [0, \infty) \rightarrow P$ is the evader's strategy
- $V(q) \subseteq P$ are the points visible from $q \in P$

Solution

- Strategy $h = h^1, \ldots, h^k$ is a solution if for every continuous $e: [0, \infty) \rightarrow P$ there exists $t \in [0, \infty), i \in \{1, \ldots, k\}$, such that $e(t) \in V(h^i(t))$.

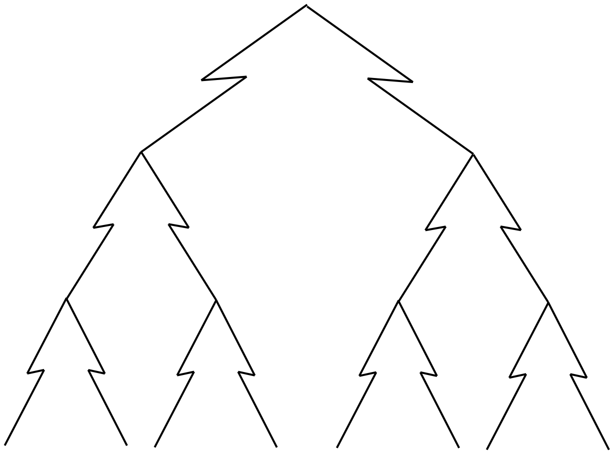
Clearing polygonal environment

Theorem (Urrutia, 1997): $O(\log n)$ hunters are always sufficient and occasionally necessary to spot a pray in polygon with n vertices.

Sufficient

- let $f(n)$ be the required number of hunters
- each polygon has a diagonal splitting it to two with $\leq \frac{2n}{3}$ vertices
- if one guard guards the diagonal, $f(n) \leq f\left(\frac{2n}{3}\right) + 1$
- from master theorem, $f(n) \in O(\log n)$

Necessary



Clearing polygonal environment

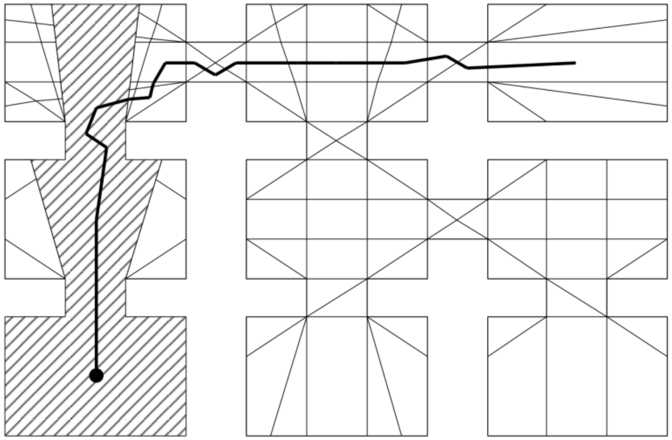
Guibas, L. J., Latombe, J.-C., Lavalle, et al.: Visibility-Based Pursuit-Evasion in a Polygonal Environment. WADS, 1997

- hunter and play setting - we assume a **single hunter**
- critical event analysis (similar to event-based simulation)

Definitions

- information state $\eta = (x, S); x \in P, S \subseteq P$ are pursuer/evader positions
- $\Psi(\eta, h, t_0, t_1)$ is the inf. state after executing h from η during $[t_0, t_1]$
- region $D \subseteq P$ is conservative, if for all continuous $h_1, h_2: [t_0, t_1] \rightarrow D$ $h_1(t_0) = h_2(t_0)$ & $h_1(t_1) = h_2(t_1) \Rightarrow \Psi(\eta, h_1, t_0, t_1) = \Psi(\eta, h_2, t_0, t_1)$

Clearing polygonal environment



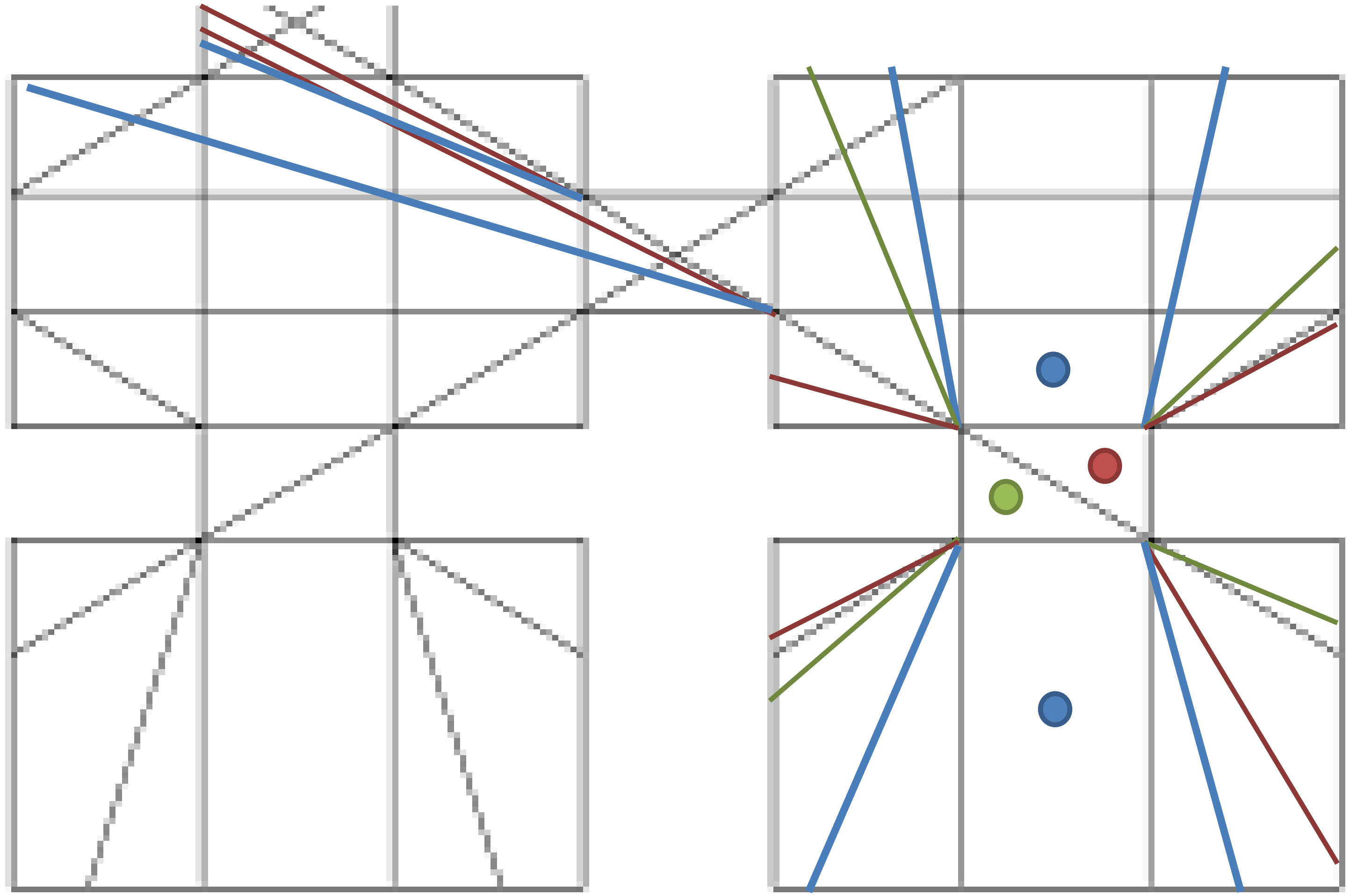
Extend the edges

- obstacle edges in both directions
- pairs of vertices outwards

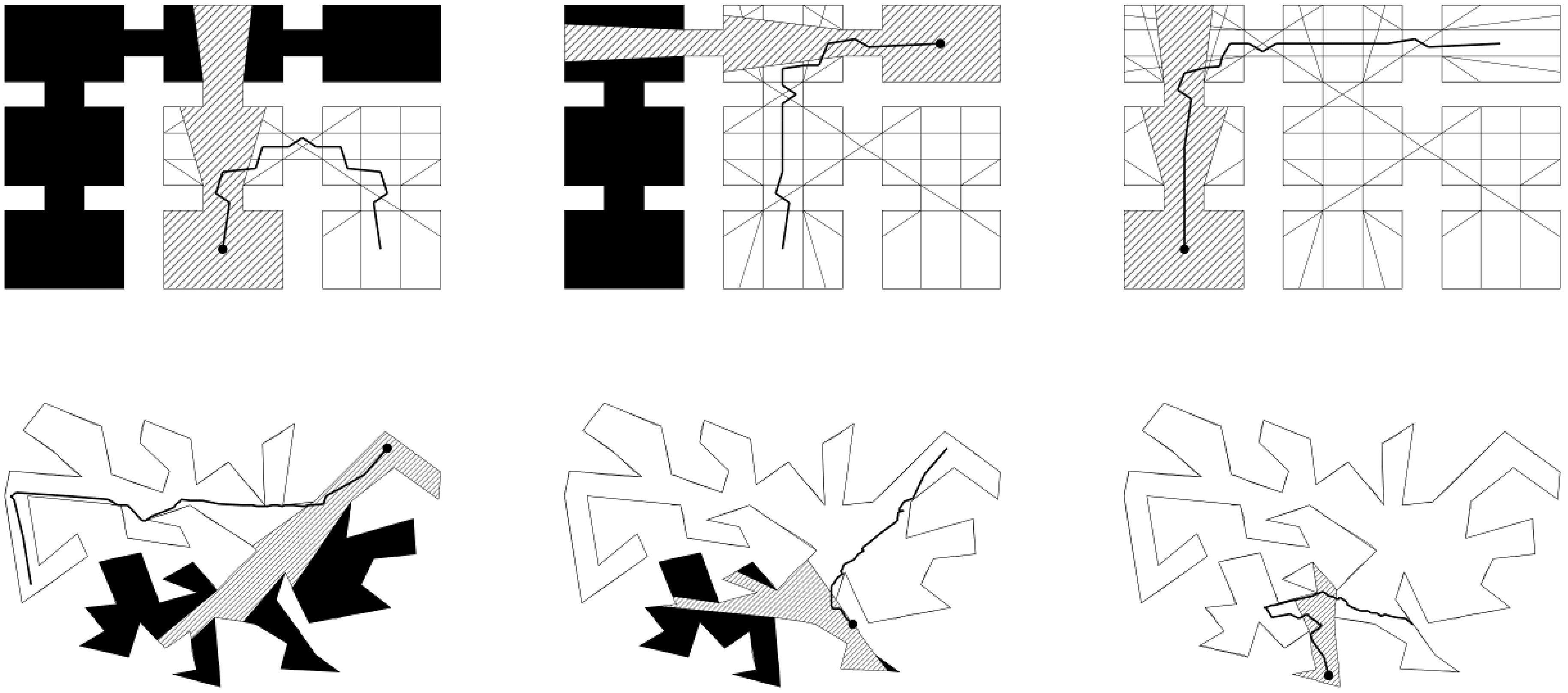
Search graph

- adjacent cell graph
- gap edge labeling: “1” contaminated, “0” clear
- corresponding gap edges determine change in labeling

Gap edge labeling



Clearing polygonal environment



Quiz: goo.gl/3S8nHh

Visibility-based tracking

graph of locations (V, E)

visibility relation $Sees(v_1, v_2)$

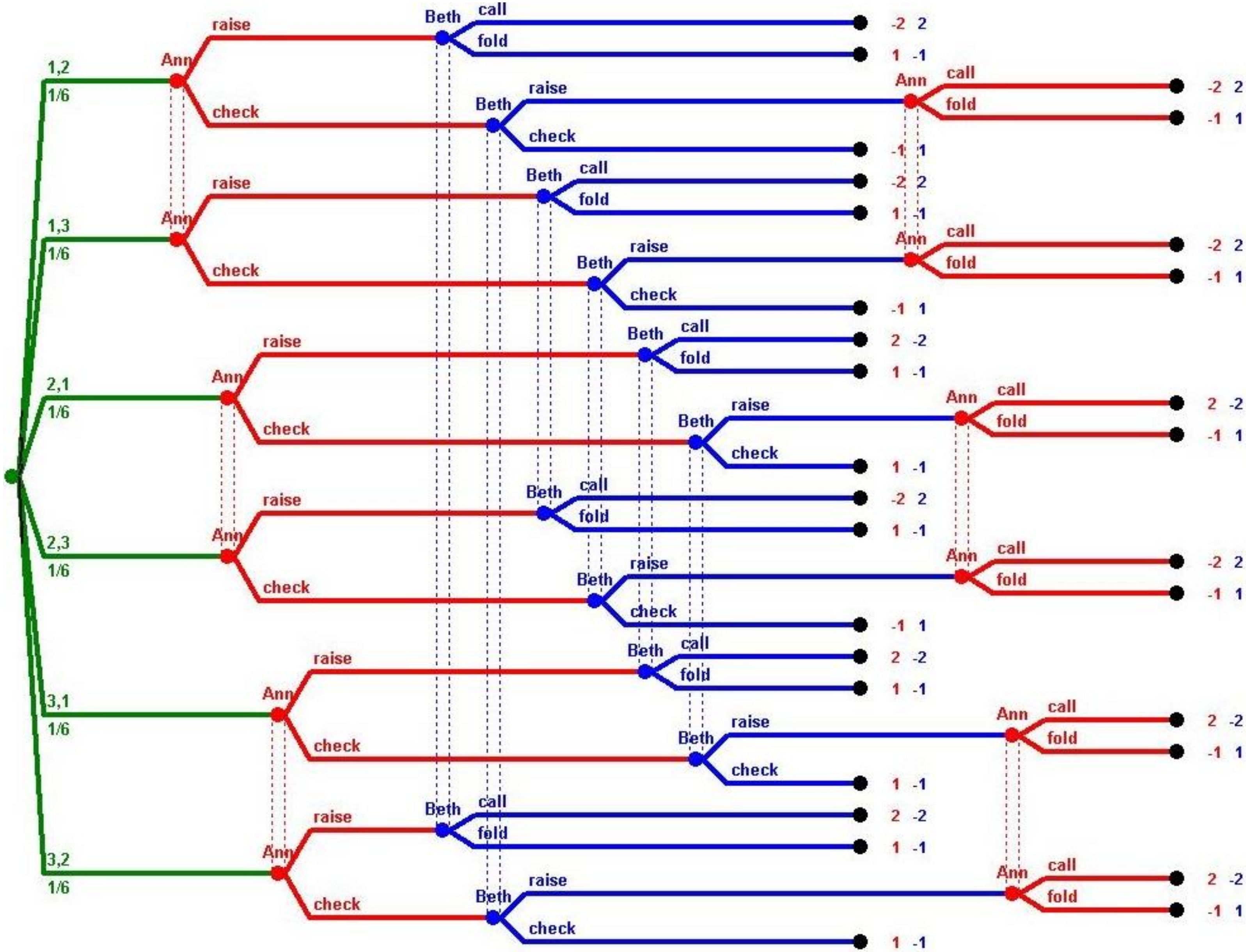
k pursuers, 1 evader

- both move on the graph
- both unit speed

Goal

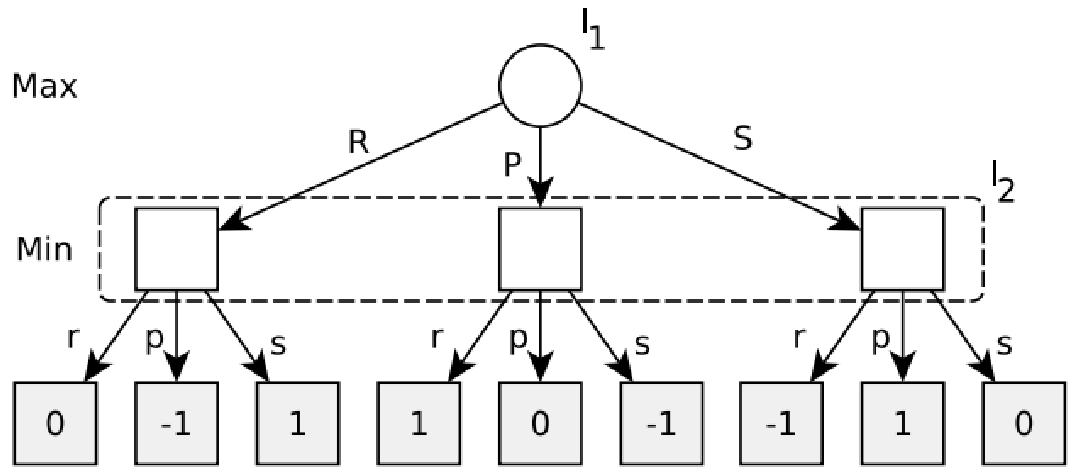
- See as often as possible
- Minimize the set of possible positions

Extensive form game

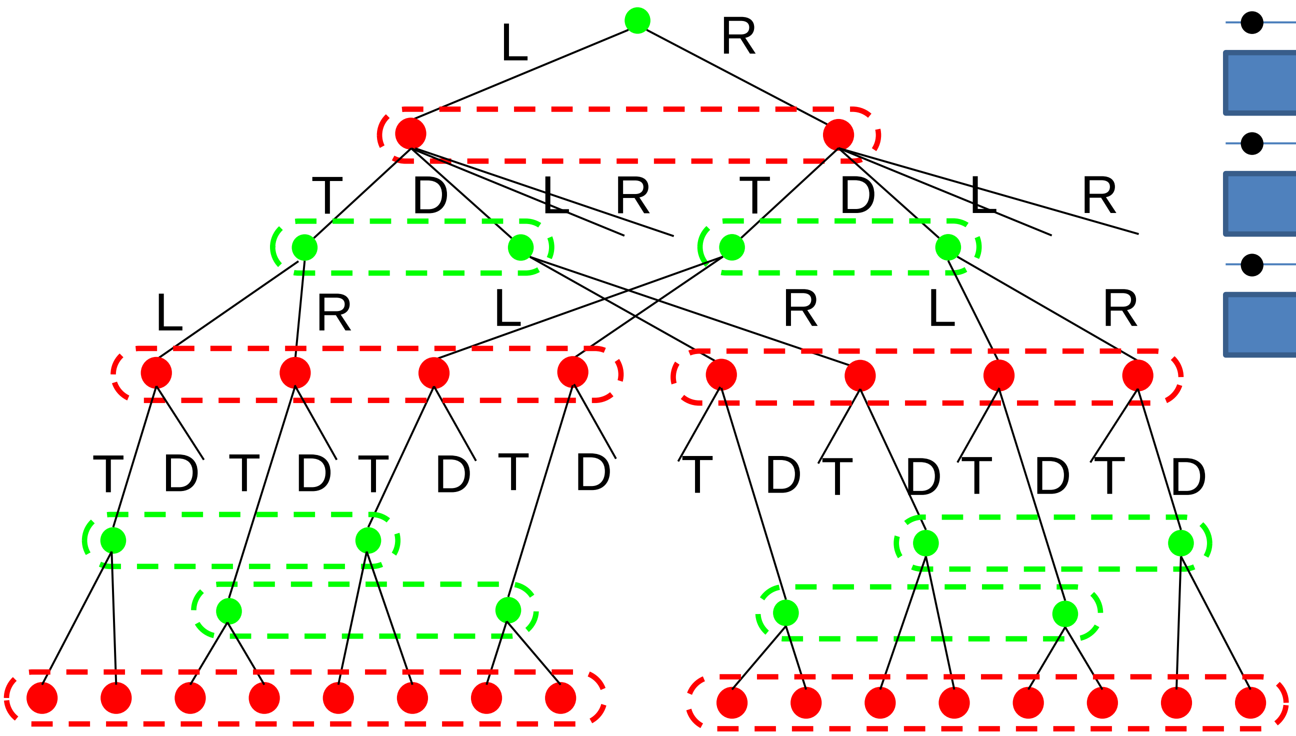


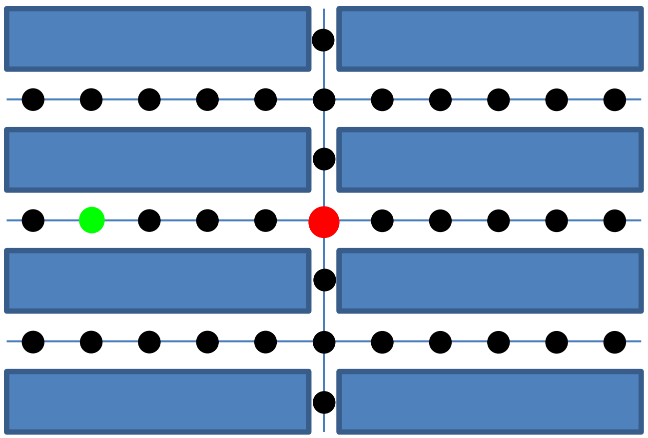
Simultaneous moves in EFG

	r	p	s
R	0	−1	1
P	1	0	−1
S	−1	1	0

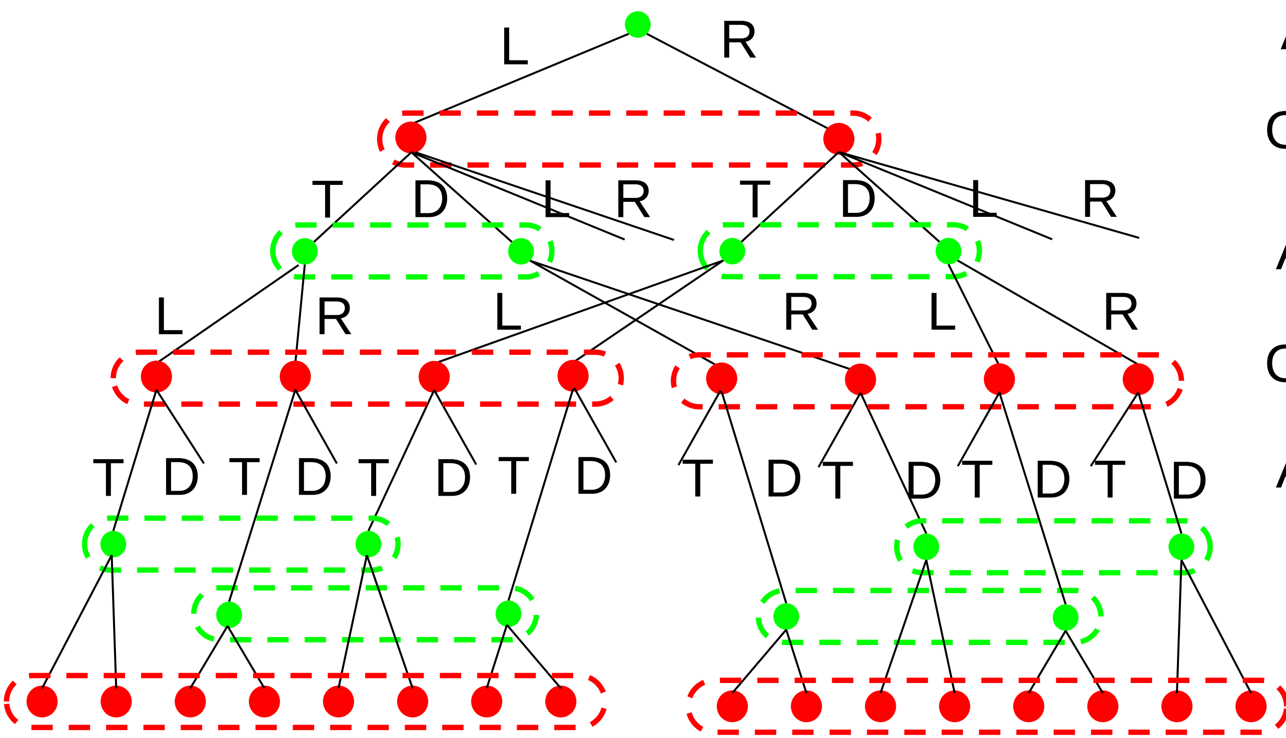


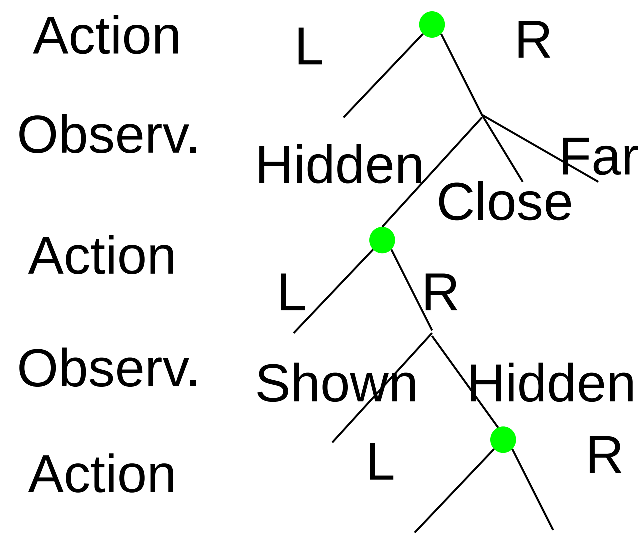
Pursuit evasion as EFG





EFG vs. Information Set Tree

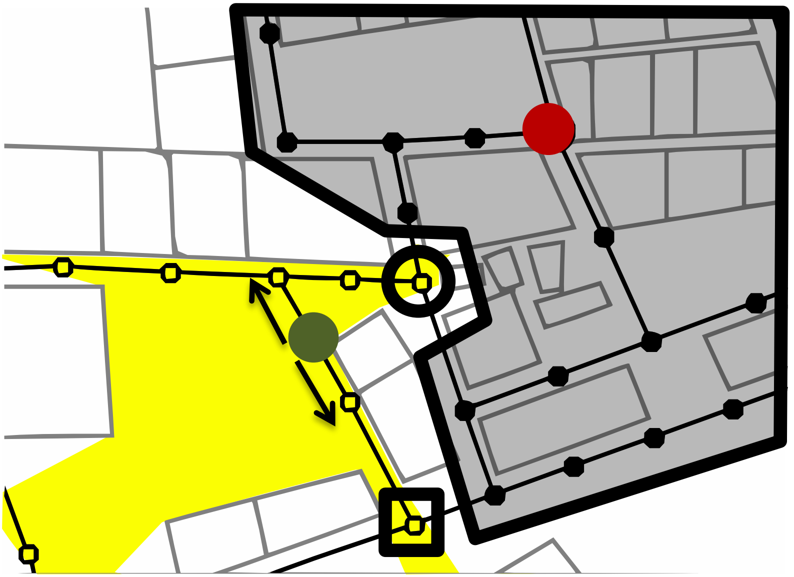


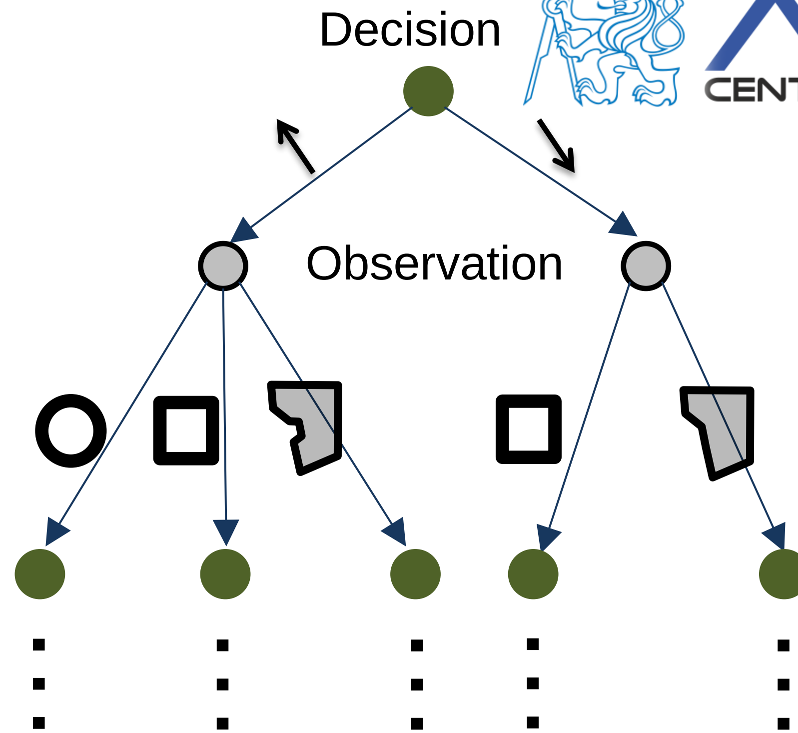


Nodes in IST are Info. Sets in EFG

+ IST is much smaller
+ solved as perfect information

- overly pessimistic (worst possible observation)





Relaxed look-ahead heuristic (Raboin at al. 2011)

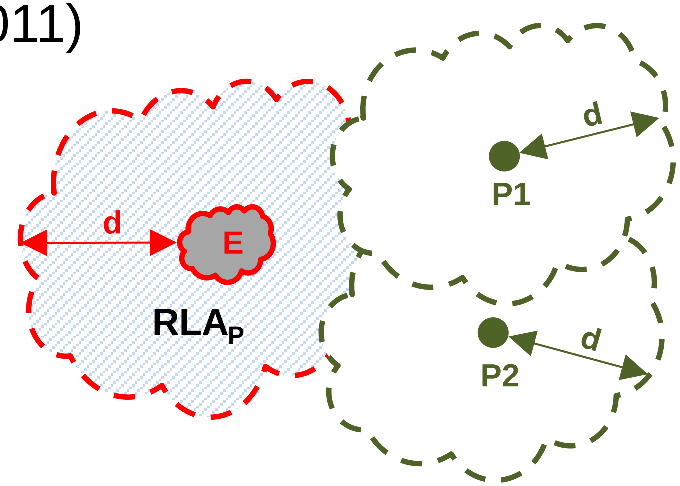
|positions reachable by evader

- positions that can be possibly seen|

evader can be on worst possible position

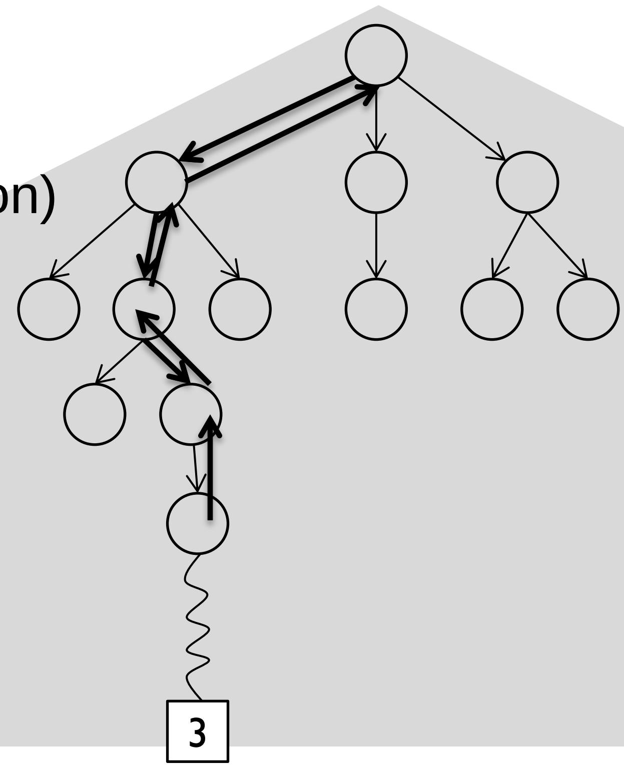
pursuers can be everywhere at once

usable in iterative deepening minimax or MCTS



(Perfect information) Monte Carlo tree search

Selection
Expansion
Simulation (evaluation)
Backpropagation



UCT selects actions based on $\arg\max_i \quad v_i + C\sqrt{\frac{\sum_j n_j}{n_i}}$

Summary

Static camera position

Camera switching

Capturing spotting fast evader

Tracking realistic evader