Real Time Search in Dynamic Worlds

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Real Time Search in Dynamic Worlds

• Real Time Search
  – Search that interleaves planning and execution of the plan
  – Hard constraint on the amount of planning that can be done each time step

• Dynamic Worlds
  – Worlds in which changes occur
  – Increases or decreases in edge cost(s)
Real Time Search in Dynamic Worlds

- Video Games
- Robotics
- Agents must return an action within a bounded time
- Doors, Bridges, Walls
Problem

• Solutions to Dynamism in Real Time Search
  – Run a real time search algorithm repetitively
    • No real time algorithm designed to work in dynamic worlds
    • Do not account for edge cost decreases
Outline

• Problem

• Previous Work
  – LSS-LRTA* – real time search
    • agent centered search
  – D* Lite – non-real time, dynamic search

• Solution - Real Time D* Lite (RTD*)

• Empirical Evaluation
Previous Work: LSS-LRTA*

- Repetitive agent centered search
- Uses A* lookahead for agent centered search
- Moves towards most promising node on the fringe of the agent centered search
- Updates cached h values of all states in local search space with Dijkstra’s algorithm
- Avoids local minima through these cached values
LSS-LRTA* Video
Previous Work: D* Lite

• Dynamic non-real time search algorithm
• Search backwards from goal to agent
• When edge cost(s) change reuses previous search
D* Lite Video
Solution: Real Time D* Lite

- Real Time
- Dynamic
- Do D* Lite
  - Stop before computation limit reached
  - Do some agent centered search
  - Resume
- Bidirectional Search
  - Use D* Lite to search from goal to agent
    - Global search
  - Use LSS-LRTA* to search from agent to goal
    - Agent centered search
Solution: Real Time D* Lite

• Combine a real time search algorithm with a dynamic search algorithm
Solution: Real Time D* Lite

• Persist global search through planning phase
• Move based on agent centered search when the global search does not have a complete path
• Move based on global search once complete path from goal to agent is found
• Computation limit divided between global and local search based on ratio parameter
Real Time D* Lite Video
Properties of Real Time D* Lite

• Complete
• Time complexity
  – Single step constant time
• Space complexity
  – Inherits from underlying algorithms
Empirical Evaluation

• Measure to evaluate a solution?
  – Time steps taken to reach goal
  – Equivalent to trajectory/path length for LSS-LRTA*, RTD*

• What algorithms used for comparison?
• LSS-LRTA*
  – Not designed to handle edge cost decreases
  – Still functions in worlds with decreases
  – May not notice new paths
Empirical Evaluation

• Quality Bounds?
• Two variants of D* Lite
  – Non-Real Time D* Lite
    • Gives us the trajectory length of RTD* as the computation limit approaches infinity
  – Naïve real time version, RTD* NoOp
    • Agent returns do not move action after each planning phase
    • Cost of solution increases by one each time if just waiting there
    • We need to do better than this, otherwise just run D* Lite without the real time constraint
Empirical Evaluation

• Two domains
  – Initially unknown, static world pathfinding
    • Warcraft maps
  – Fully observable, dynamic world pathfinding
    • Rooms generated with doors opening and closing
    • Path to goal always guaranteed
Initially Unknown, Static World Pathfinding
Initially Unknown, Static World Pathfinding Video
Initially Unknown, Static World Pathfinding

Time Steps (relative to A*)

Expansion Limit

- NoOp RTD*
- Non-RTD*

1
2
3
10
100

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Initially Unknown, Static World Pathfinding

Real Time Search in Dynamic Worlds

David Bond (UNH)
Fully Observable, Dynamic World Pathfinding
Fully Observable, Dynamic World Pathfinding

Expansion Limit

Time Steps (relative to A*)

Non-RTD*
Fully Observable, Dynamic World Pathfinding

Time Steps (relative to A*)

Expansion Limit

LSS-LRTA*
RTD*
Non-RTD*
Conclusion

• The first algorithm designed for dynamic real time worlds
• Modular and expandable
• Visit http://mokon.net/mai.aspx for source code and detailed results