



FALMOUTH  
UNIVERSITY



COMP280: Specialisms in Creative Computing

# 8: Navigation

# Pathfinding



# The problem

- ▶ We have a **graph**

# The problem

- ▶ We have a **graph**
  - ▶ **Nodes** (points)

# The problem

- ▶ We have a **graph**
  - ▶ **Nodes** (points)
  - ▶ **Edges** (lines between points, each with a **weight**)

# The problem

- ▶ We have a **graph**
  - ▶ **Nodes** (points)
  - ▶ **Edges** (lines between points, each with a **weight**)
- ▶ E.g. a road map

# The problem

- ▶ We have a **graph**
  - ▶ **Nodes** (points)
  - ▶ **Edges** (lines between points, each with a **weight**)
- ▶ E.g. a road map
  - ▶ Nodes = addresses

# The problem

- ▶ We have a **graph**
  - ▶ **Nodes** (points)
  - ▶ **Edges** (lines between points, each with a **weight**)
- ▶ E.g. a road map
  - ▶ Nodes = addresses
  - ▶ Edges = roads



# The problem

- ▶ We have a **graph**
  - ▶ **Nodes** (points)
  - ▶ **Edges** (lines between points, each with a **weight**)
- ▶ E.g. a road map
  - ▶ Nodes = addresses
  - ▶ Edges = roads
- ▶ E.g. a tile-based 2D game

# The problem

- ▶ We have a **graph**
  - ▶ **Nodes** (points)
  - ▶ **Edges** (lines between points, each with a **weight**)
- ▶ E.g. a road map
  - ▶ Nodes = addresses
  - ▶ Edges = roads
- ▶ E.g. a tile-based 2D game
  - ▶ Nodes = grid squares

# The problem

- ▶ We have a **graph**
  - ▶ **Nodes** (points)
  - ▶ **Edges** (lines between points, each with a **weight**)
- ▶ E.g. a road map
  - ▶ Nodes = addresses
  - ▶ Edges = roads
- ▶ E.g. a tile-based 2D game
  - ▶ Nodes = grid squares
  - ▶ Edges = connections between adjacent squares

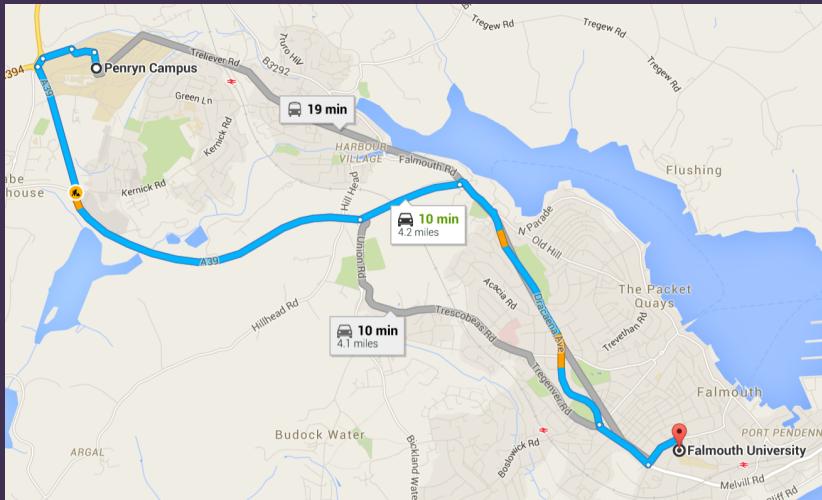
# The problem

- ▶ We have a **graph**
  - ▶ **Nodes** (points)
  - ▶ **Edges** (lines between points, each with a **weight**)
- ▶ E.g. a road map
  - ▶ Nodes = addresses
  - ▶ Edges = roads
- ▶ E.g. a tile-based 2D game
  - ▶ Nodes = grid squares
  - ▶ Edges = connections between adjacent squares
- ▶ Given two nodes *A* and *B*, find the **shortest path** from *A* to *B*

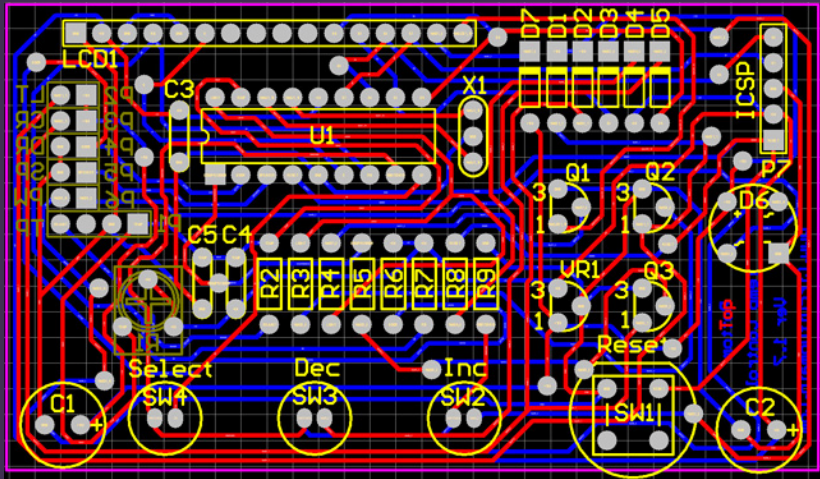
# The problem

- ▶ We have a **graph**
  - ▶ **Nodes** (points)
  - ▶ **Edges** (lines between points, each with a **weight**)
- ▶ E.g. a road map
  - ▶ Nodes = addresses
  - ▶ Edges = roads
- ▶ E.g. a tile-based 2D game
  - ▶ Nodes = grid squares
  - ▶ Edges = connections between adjacent squares
- ▶ Given two nodes *A* and *B*, find the **shortest path** from *A* to *B*
  - ▶ “Shortest” in terms of edge weights — could be distance, time, fuel cost, ...

# Applications of pathfinding



# Applications of pathfinding



# Applications of pathfinding





# Applications of pathfinding



# Applications of pathfinding



# Pathfinding as search

# Pathfinding as search

- ▶ Basic idea: build a **spanning tree** for the graph

# Pathfinding as search

- ▶ Basic idea: build a **spanning tree** for the graph
- ▶ Root node is A (the start node)

# Pathfinding as search

- ▶ Basic idea: build a **spanning tree** for the graph
- ▶ Root node is A (the start node)
- ▶ Edges in the tree are a **subset** of edges of the graph

# Pathfinding as search

- ▶ Basic idea: build a **spanning tree** for the graph
- ▶ Root node is  $A$  (the start node)
- ▶ Edges in the tree are a **subset** of edges of the graph
- ▶ Once the tree includes  $B$ , we can read off the path from  $A$  to  $B$

# Pathfinding as search

- ▶ Basic idea: build a **spanning tree** for the graph
- ▶ Root node is  $A$  (the start node)
- ▶ Edges in the tree are a **subset** of edges of the graph
- ▶ Once the tree includes  $B$ , we can read off the path from  $A$  to  $B$
- ▶ Need to keep track of two sets of nodes:



# Pathfinding as search

- ▶ Basic idea: build a **spanning tree** for the graph
- ▶ Root node is  $A$  (the start node)
- ▶ Edges in the tree are a **subset** of edges of the graph
- ▶ Once the tree includes  $B$ , we can read off the path from  $A$  to  $B$
- ▶ Need to keep track of two sets of nodes:
  - ▶ **Open set**: nodes within 1 edge of the tree, which could be added next

# Pathfinding as search

- ▶ Basic idea: build a **spanning tree** for the graph
- ▶ Root node is  $A$  (the start node)
- ▶ Edges in the tree are a **subset** of edges of the graph
- ▶ Once the tree includes  $B$ , we can read off the path from  $A$  to  $B$
- ▶ Need to keep track of two sets of nodes:
  - ▶ **Open set**: nodes within 1 edge of the tree, which could be added next
  - ▶ **Closed set**: nodes which have been added to the tree, and shouldn't be revisited (otherwise we could get stuck in an infinite loop)

# Graph traversal

# Graph traversal

- ▶ **Depth-first** or **breadth-first**

# Graph traversal

- ▶ **Depth-first** or **breadth-first**
- ▶ Can be implemented with the open set as a **stack** or a **queue** respectively

# Graph traversal

- ▶ **Depth-first** or **breadth-first**
- ▶ Can be implemented with the open set as a **stack** or a **queue** respectively
- ▶ Inefficient — generally has to explore the **entire map**

# Graph traversal

- ▶ **Depth-first** or **breadth-first**
- ▶ Can be implemented with the open set as a **stack** or a **queue** respectively
- ▶ Inefficient — generally has to explore the **entire map**
- ▶ Finds a path, but probably not the **shortest**

# Graph traversal

- ▶ **Depth-first** or **breadth-first**
- ▶ Can be implemented with the open set as a **stack** or a **queue** respectively
- ▶ Inefficient — generally has to explore the **entire map**
- ▶ Finds a path, but probably not the **shortest**
- ▶ Third type of traversal: **best-first**



# Graph traversal

- ▶ **Depth-first** or **breadth-first**
- ▶ Can be implemented with the open set as a **stack** or a **queue** respectively
- ▶ Inefficient — generally has to explore the **entire map**
- ▶ Finds a path, but probably not the **shortest**
- ▶ Third type of traversal: **best-first**
  - ▶ “Best” according to some heuristic evaluation

# Graph traversal

- ▶ **Depth-first** or **breadth-first**
- ▶ Can be implemented with the open set as a **stack** or a **queue** respectively
- ▶ Inefficient — generally has to explore the **entire map**
- ▶ Finds a path, but probably not the **shortest**
- ▶ Third type of traversal: **best-first**
  - ▶ “Best” according to some heuristic evaluation
  - ▶ Often implemented with the open set as a **priority queue** — a data structure optimised for finding the **highest priority** item

# Greedy search

# Greedy search

- ▶ Always try to move **closer** to the goal

# Greedy search

- ▶ Always try to move **closer** to the goal
- ▶ Visit the node whose **distance to the goal** is **minimal**

# Greedy search

- ▶ Always try to move **closer** to the goal
- ▶ Visit the node whose **distance to the goal** is **minimal**
- ▶ E.g. **Euclidean** distance (straight line distance — Pythagoras' Theorem)

# Greedy search

- ▶ Always try to move **closer** to the goal
- ▶ Visit the node whose **distance to the goal** is **minimal**
- ▶ E.g. **Euclidean** distance (straight line distance — Pythagoras' Theorem)
- ▶ Doesn't handle **dead ends** well

# Greedy search

- ▶ Always try to move **closer** to the goal
- ▶ Visit the node whose **distance to the goal** is **minimal**
- ▶ E.g. **Euclidean** distance (straight line distance — Pythagoras' Theorem)
- ▶ Doesn't handle **dead ends** well
- ▶ Not guaranteed to find the **shortest** path



# Dijkstra's algorithm

# Dijkstra's algorithm

- Let  $g(x)$  be the sum of edge weights of the path found from the start to  $x$

# Dijkstra's algorithm

- ▶ Let  $g(x)$  be the sum of edge weights of the path found from the start to  $x$
- ▶ Choose a node that minimises  $g(x)$

# Dijkstra's algorithm

- ▶ Let  $g(x)$  be the sum of edge weights of the path found from the start to  $x$
- ▶ Choose a node that minimises  $g(x)$
- ▶ Needs to handle cases where a shorter path to a node is discovered later in the search

# Dijkstra's algorithm

- ▶ Let  $g(x)$  be the sum of edge weights of the path found from the start to  $x$
- ▶ Choose a node that minimises  $g(x)$
- ▶ Needs to handle cases where a shorter path to a node is discovered later in the search
- ▶ **Is** guaranteed to find the shortest path

# Dijkstra's algorithm

- ▶ Let  $g(x)$  be the sum of edge weights of the path found from the start to  $x$
- ▶ Choose a node that minimises  $g(x)$
- ▶ Needs to handle cases where a shorter path to a node is discovered later in the search
- ▶ **Is** guaranteed to find the shortest path
- ▶ ... but is not the most efficient algorithm for doing so

# A\* search

# A\* search

- ▶ Let  $h(x)$  be an estimate of the distance from  $x$  to the goal (as in greedy search)



# A\* search

- ▶ Let  $h(x)$  be an estimate of the distance from  $x$  to the goal (as in greedy search)
- ▶ Let  $g(x)$  be the distance of the path found from the start to  $x$  (as in Dijkstra's algorithm)

# A\* search

- ▶ Let  $h(x)$  be an estimate of the distance from  $x$  to the goal (as in greedy search)
- ▶ Let  $g(x)$  be the distance of the path found from the start to  $x$  (as in Dijkstra's algorithm)
- ▶ Choose a node that minimises  $g(x) + h(x)$

# Properties of $A^*$ search

- ▶  $A^*$  is **guaranteed** to find the shortest path if the distance estimate  $h(x)$  is **admissible**

# Properties of A\* search

- ▶ A\* is **guaranteed** to find the shortest path if the distance estimate  $h(x)$  is **admissible**
- ▶ Essentially, **admissible** means it must be an **underestimate**

# Properties of A\* search

- ▶ A\* is **guaranteed** to find the shortest path if the distance estimate  $h(x)$  is **admissible**
- ▶ Essentially, **admissible** means it must be an **underestimate**
  - ▶ E.g. straight line Euclidean distance is clearly an underestimate for actual travel distance

# Properties of A\* search

- ▶ A\* is **guaranteed** to find the shortest path if the distance estimate  $h(x)$  is **admissible**
- ▶ Essentially, **admissible** means it must be an **underestimate**
  - ▶ E.g. straight line Euclidean distance is clearly an underestimate for actual travel distance
- ▶ The more accurate  $h(x)$  is, the more efficient the search

# Properties of $A^*$ search

- ▶  $A^*$  is **guaranteed** to find the shortest path if the distance estimate  $h(x)$  is **admissible**
- ▶ Essentially, **admissible** means it must be an **underestimate**
  - ▶ E.g. straight line Euclidean distance is clearly an underestimate for actual travel distance
- ▶ The more accurate  $h(x)$  is, the more efficient the search
  - ▶ E.g.  $h(x) = 0$  is admissible (and gives Dijkstra's algorithm), but not very helpful

# Properties of A\* search

- ▶ A\* is **guaranteed** to find the shortest path if the distance estimate  $h(x)$  is **admissible**
- ▶ Essentially, **admissible** means it must be an **underestimate**
  - ▶ E.g. straight line Euclidean distance is clearly an underestimate for actual travel distance
- ▶ The more accurate  $h(x)$  is, the more efficient the search
  - ▶ E.g.  $h(x) = 0$  is admissible (and gives Dijkstra's algorithm), but not very helpful
- ▶  $h(x)$  is a **heuristic**



# Properties of $A^*$ search

- ▶  $A^*$  is **guaranteed** to find the shortest path if the distance estimate  $h(x)$  is **admissible**
- ▶ Essentially, **admissible** means it must be an **underestimate**
  - ▶ E.g. straight line Euclidean distance is clearly an underestimate for actual travel distance
- ▶ The more accurate  $h(x)$  is, the more efficient the search
  - ▶ E.g.  $h(x) = 0$  is admissible (and gives Dijkstra's algorithm), but not very helpful
- ▶  $h(x)$  is a **heuristic**
  - ▶ In AI, a heuristic is an estimate based on human intuition

# Properties of A\* search

- ▶ A\* is **guaranteed** to find the shortest path if the distance estimate  $h(x)$  is **admissible**
- ▶ Essentially, **admissible** means it must be an **underestimate**
  - ▶ E.g. straight line Euclidean distance is clearly an underestimate for actual travel distance
- ▶ The more accurate  $h(x)$  is, the more efficient the search
  - ▶ E.g.  $h(x) = 0$  is admissible (and gives Dijkstra's algorithm), but not very helpful
- ▶  $h(x)$  is a **heuristic**
  - ▶ In AI, a heuristic is an estimate based on human intuition
  - ▶ Heuristics are often used to prioritise search, i.e. explore the most promising options first

# Tweaking A\*

# Tweaking A\*

- ▶ Can change how  $g(x)$  is calculated

# Tweaking A\*

- ▶ Can change how  $g(x)$  is calculated
  - ▶ Increased movement cost for rough terrain, water, lava...

# Tweaking A\*

- ▶ Can change how  $g(x)$  is calculated
  - ▶ Increased movement cost for rough terrain, water, lava...
  - ▶ Penalty for changing direction

# Tweaking $A^*$

- ▶ Can change how  $g(x)$  is calculated
  - ▶ Increased movement cost for rough terrain, water, lava...
  - ▶ Penalty for changing direction
- ▶ Different  $h(x)$  can lead to different paths (if there are multiple “shortest” paths)

# String pulling



# String pulling

- ▶ Paths restricted to edges can look unnatural

# String pulling

- ▶ Paths restricted to edges can look unnatural
- ▶ Intuition: visualise the path as a string, then pull both ends to make it taut

# String pulling

- ▶ Paths restricted to edges can look unnatural
- ▶ Intuition: visualise the path as a string, then pull both ends to make it taut
- ▶ Simple algorithm:

# String pulling

- ▶ Paths restricted to edges can look unnatural
- ▶ Intuition: visualise the path as a string, then pull both ends to make it taut
- ▶ Simple algorithm:
  - ▶ Found path is  $p[0], p[1], \dots, p[n]$

# String pulling

- ▶ Paths restricted to edges can look unnatural
- ▶ Intuition: visualise the path as a string, then pull both ends to make it taut
- ▶ Simple algorithm:
  - ▶ Found path is  $p[0], p[1], \dots, p[n]$
  - ▶ If the line from  $p[i]$  to  $p[i+2]$  is unobstructed, remove point  $p[i+1]$

# String pulling

- ▶ Paths restricted to edges can look unnatural
- ▶ Intuition: visualise the path as a string, then pull both ends to make it taut
- ▶ Simple algorithm:
  - ▶ Found path is  $p[0], p[1], \dots, p[n]$
  - ▶ If the line from  $p[i]$  to  $p[i+2]$  is unobstructed, remove point  $p[i+1]$
  - ▶ Repeat until there are no more points that can be removed

# Navigation meshes



# Pathfinding in videogames



# Pathfinding in videogames

- ▶ A\* works on any **graph**

# Pathfinding in videogames

- ▶ A\* works on any **graph**
- ▶ But what if the game world is not a graph? E.g. complex 3D environments

# Waypoint navigation



# Waypoint navigation

- Manually place graph nodes in the world



# Waypoint navigation

- ▶ Manually place graph nodes in the world
- ▶ Place them at key points, e.g. in doorways, around obstacles



# Waypoint navigation

- ▶ Manually place graph nodes in the world
- ▶ Place them at key points, e.g. in doorways, around obstacles
- ▶ Works, but...



# Waypoint navigation



- ▶ Manually place graph nodes in the world
- ▶ Place them at key points, e.g. in doorways, around obstacles
- ▶ Works, but...
  - ▶ More work for level designers

# Waypoint navigation



- ▶ Manually place graph nodes in the world
- ▶ Place them at key points, e.g. in doorways, around obstacles
- ▶ Works, but...
  - ▶ More work for level designers
  - ▶ Requires lots of testing and tweaking to get natural-looking results



# Waypoint navigation



- ▶ Manually place graph nodes in the world
- ▶ Place them at key points, e.g. in doorways, around obstacles
- ▶ Works, but...
  - ▶ More work for level designers
  - ▶ Requires lots of testing and tweaking to get natural-looking results
  - ▶ No good for dynamic environments

# Navigation meshes



# Navigation meshes

- Automatically generate navigation graph from level geometry



# Navigation meshes

- ▶ Automatically generate navigation graph from level geometry
- ▶ Basic idea:



# Navigation meshes



- ▶ Automatically generate navigation graph from level geometry
- ▶ Basic idea:
  - ▶ Filter level geometry to those polygons which are **passable** (i.e. floors, not walls/ceilings/obstacles)

# Navigation meshes



- ▶ Automatically generate navigation graph from level geometry
- ▶ Basic idea:
  - ▶ Filter level geometry to those polygons which are **passable** (i.e. floors, not walls/ceilings/obstacles)
  - ▶ Generate graph from polygons

# Navigation meshes



- ▶ Automatically generate navigation graph from level geometry
- ▶ Basic idea:
  - ▶ Filter level geometry to those polygons which are **passable** (i.e. floors, not walls/ceilings/obstacles)
  - ▶ Generate graph from polygons
- ▶ Unity and Unreal have good built-in navigation mesh generation

# Following the path



# Following the path

- ▶ **Steering:** don't have your AI agent follow the path exactly, but instead try to stay close to it

# Following the path

- ▶ **Steering**: don't have your AI agent follow the path exactly, but instead try to stay close to it
- ▶ **Funnelling**: like string pulling but for navigation meshes

# Following the path

- ▶ **Steering:** don't have your AI agent follow the path exactly, but instead try to stay close to it
- ▶ **Funnelling:** like string pulling but for navigation meshes
- ▶ **Dynamic environments:** may need to re-run pathfinder if environment changes (e.g. movable obstacles, destructible terrain)

# Following the path

- ▶ **Steering**: don't have your AI agent follow the path exactly, but instead try to stay close to it
- ▶ **Funnelling**: like string pulling but for navigation meshes
- ▶ **Dynamic environments**: may need to re-run pathfinder if environment changes (e.g. movable obstacles, destructible terrain)
- ▶ **Avoidance**: how to have NPCs avoid running into each other?

# Workshop

