Task Group Allocation for Solving Multi-Load Agent Pickup and Delivery problem

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ABSTRACT

This document outlines the formatting instructions for submissions to AAMAS-2025. You can use its source file as a template when writing your own paper. It is based on the file 'sample-sigconf.tex' distributed with the ACM article template for LaTeX.

KEYWORDS

Multi-load agent, Pickup and delivery problem, Task allocation

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1 INTRODUCTION

The multi-load agent pickup and delivery problem (MLAPD) is a variant of the pickup and delivery problem which is a well-known combinatorial optimization problem in the field of logistics and transportation. In the MLAPD problem, there are multiple agents, each of which can carry multiple tasks at the same time. The goal is to allocate tasks to agents to optimize the completion time of all tasks. The MLAPD problem is a NP-hard problem, and it is difficult to solve it optimally in polynomial time [1].

2 RELATED WORK

3 PROBLEM DEFINITION

In this section, we introduce the multi-load agent pickup and delivery problem, which we address in this paper. Before this, we first give the definitions of map, task, agent, comparative metrics and MLAPD problem.

Definition 3.1 (Map). A map $G = (V, E)$ is the , whose vertices V correspond to locations and edges E represent edges between adjoining locations. The shortest distance between two locations v_i and v_j is denoted as $dis(v_i, v_j)$.

Definition 3.2 (Task). A task $\tau \in \Gamma$ is a tuple $< v_\tau^s, v_\tau^g, t_\tau^r, t_\tau^d, t_\tau^c >$, where v_τ^s and v_τ^g are the pickup location and delivery location, respectively. t_τ^r, t_τ^d and t_τ^c are the release time, deadline and completed time, respectively.

Definition 3.3 (Agent). An agent $a \in A$ is represented as a tuple $< v_a, c_a, \Gamma_a, S_a >$, where v_a is location, c_a represents the maximum capacity, Γ_a is the set of tasks, and S_a is the schedule of Γ_a. The $S_a =< v_1, v_2, ..., v_n >$, where v_i is a pickup or delivery location of task $\tau \in \Gamma_a$.

A task $\tau \in \Gamma$ is released at t_τ^r. When system assigns τ to an agent a, a needs to reach v_τ^s before t_τ^d, and then deliver τ to v_τ^g while recording the completed time t_τ^c. If τ could not be completed before t_τ^d, then the task is considered as failed.

Definition 3.4 (Comparative metrics). In this paper, we demonstrate algorithmic superiority through three comparative metrics, service time (ST), makespan (MS) and completion ratio (CR). $ST = \sum_{\tau_i \in \Gamma} (t_{\tau_i}^c - t_{\tau_i}^r)$, is defined as the sum of differences between the completed times and the release times of all tasks. $MS = max\{t_\tau^c\}$ $(\forall \tau \in \Gamma)$ is time when last task has completed. $CR = \sum_{\tau_i \in \Gamma} X_{\tau_i} / |\Gamma|$, where X_{τ_i} is a decision variable, is completion ratio of Γ. If task τ_i is completed, then X_{τ_i} is 1; otherwise, it is 0.

Definition 3.5 (MLAPD). The multi-load agent pickup and delivery problem (MLAPD) is a tuple $P =< G, A, \Gamma >$, defined by a map G, a set of agents A, and a set of tasks Γ. Moreover, P amounts to finding the allocation of tasks to agents, which optimize three comparative indicators, (ST, MS, CR). Time is discretized into timesteps, and agents can only move to adjacent locations or wait at its current location in one timestep. However, a conflict occurs when two agents are at the same location or pass through the same edge at the same time. The time required to avoid conflicts needs to be considered, since it will affect the comparative metrics. Therefore, we assue that agents can take θ time to avoid a conflict.

4 SOLUTION

In this study, Task-Group Allocation Algorithm (TGA) is developed to solve MLAPD problem efficiently. The TGA method first analyzes the likelihood of carpooling between each task, and then divide the set of tasks into groups via K-Capacity Hierarchical Clustering Algorithm (KCHC). Then, we allocate task groups to agents.

4.1 Task Group

The biggest difference between multi-load agent and single-load agent is that multi-load agent can load multiple items at the same time. This means that multi-load agent performing a task affects the completion time of the "co-passenger" tasks which are also executed to the same agent at same time.

Example 4.1. As shown as in Figure 1, there is an agent, a, and three tasks, τ_1, τ_2 and τ_3. The agent a is located at pickup location of τ_1. The blue lines are the shortest paths for agent a to complete τ_1 and τ_2. The red lines are the shortest paths for agent a to complete τ_1 and τ_3. When we allocate τ_1 and τ_2 to the agent a, the agent a needs to take the blue paths to complete τ_1 and τ_2 by greedy strategy, and it will not impact the completion time of τ_2 but lengthen the

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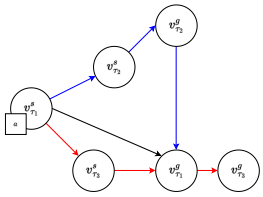
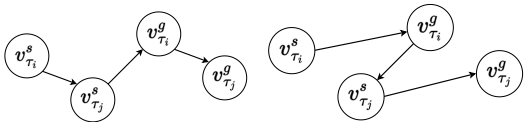


Figure 1: The impact of co-passenger tasks

completed time of τ_1. Howerver, if we allocate τ_1 and τ_3 to the agent a, a needs to take the red paths to complete τ_1 and τ_3. While it also lengthens the completed time of τ_1, it is obvious that τ_3 has less of an effect on τ_1 as compared to τ_2. Therefore, we need to consider the impact of "co-passenger" tasks when allocating tasks to agents.



(a) $Path^1_{i,j}$ (b) $Path^2_{i,j}$

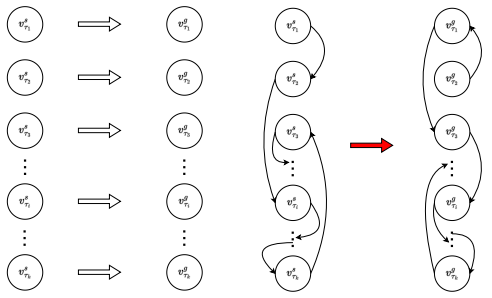
Figure 2: All possible paths of two tasks

We first analyze the likelihood of carpooling between two tasks. As shown in Figure 2, there are 6 paths to the completion of τ_i and τ_j, ignoring the location of agent. The paths are $Path^1_{i,j}$, $Path^2_{i,j}$, $Path^3_{i,j}$, $Path^4_{i,j}$, $Path^5_{i,j}$ and $Path^6_{i,j}$. Therefore, we define the carpooling chance between two tasks τ_i and τ_j as follows.

Definition 4.2. The carpooling chance between two tasks τ_i and τ_j is defined as

$$\Delta_{\tau_i,\tau_j} = min\{Path^q_{i,j}\} - dis(v^g_{\tau_i}, v^s_{\tau_i}) - dis(v^g_{\tau_j}, v^s_{\tau_j}) \quad (1)$$

where $q \in [1,6] \wedge q \in \mathbb{N}_+$. $\Delta_{i,j}$ is difference between the shortest path of two tasks and the sum of the distances between the pickup and delivery locations of the two tasks. The small $\Delta_{i,j}$ indicates that τ_i and τ_j being executed by the same agent has less impact on each other's completed time, which can efficiently optimize ST.



(a) K tasks (b) Path of K tasks

Figure 3: Path of K Tasks

Theorem 4.3. *Given a set of tasks* Γ_N,

$$Cost \leq \sum_{\tau_i \in \Gamma_N} dis(v^s_{\tau_i}, v^g_{\tau_i}) - 2 * (N-1)\Delta \quad (2)$$

Proof. this is a proof. □

4.2 K-Capacity Hierarchical Clustering

Based on Theorem 4.3, we can divide the set of tasks into groups. The K-Capacity Hierarchical Clustering Algorithm (KCHC) is proposed to divide the set of tasks into groups. The KCHC algorithm is shown in Algorithm 1.

Algorithm 1 K-Capacity Hierarchical Clustering Algorithm

Require: N tasks Γ_N, K capacity.
Ensure: M task groups Γ_M.
$M \leftarrow 0$

REFERENCES

[1] Xiaoshan Bai, Andres Fielbaum, Maximilian Kronmüller, Luzia Knoedler, and Javier Alonso-Mora. 2022. Group-based distributed auction algorithms for multi-robot task assignment. *IEEE Transactions on Automation Science and Engineering* 20, 2 (2022), 1292–1303.