Artificial Intelligence Solutions for Pathfinding for 2D Grids

*by Karl Ward*

# Introduction

I have been tasked with researching and implementing a 2D grid-based pathfinding solution in the form of an artificial neural network (ANN) or a genetic algorithm (GA). I have researched and compared the different solutions to this problem and have in turn implemented and tested the algorithm in a variety of situations. So far, I have implemented an A\* pathfinding algorithm which uses the Euclidean distance for the heuristic.

# Problem & Research

Melbourne Intelligent Computer Games has assigned the task of researching an ANN or GA that can provide an alternative to the deterministic A\* pathfinding implementation. During my research I have found a variety of peer-reviewed papers that consider the same grid style that

When researching this I will need to look for an algorithm which can be used on a 2D aligned grid and both fast and practical for the purposes of a real-time game. First, I researched genetic algorithms and found 2 suitable papers on the subject and then I had a look a neural network implementation and found quite a contrast between the two approaches.

Neural Network Research

The paper **Neural Networks for Real Time Pathfinding in Games** [1] presents a simple neural network solution that uses a simple 3-layer network. In this paper the authors acknowledge the need for real-time pathfinding in video games and they consider a changing world directly.

The advantages of this implementation are that it can avoid static and dynamic game objects by trying to give the neural network real-time awareness of the search-path’s surrounding cells. In this study the authors have already tested the effectiveness of the neural networking using various neuron counts on the hidden layer and have found that 4 neurons happen to be the fastest. This neural network’s weights are then evolved using a genetic algorithm.

The cons of this approach are that their implementation focus highly on a dynamic environment. Based on the task at hand this would be a lot of extra processing on features of the environment that don’t exist in our maps. Additionally, the authors conclusions have found that although this is possible using this approach it can become quite a slow process, and they propose a solution to be one ANN for travelling towards the target and another ANN for avoid obstacles, but this is out of the scope of the assignment.

Genetic Algorithm Research

In **Using a Genetic Algorithm to Explore A\*-like Pathfinding Algorithms** they approach the problem with a genetic algorithm. In this paper they use the idea of naval ships as obstacles within the grid, and they use a genetic algorithm to analyses around themselves and has a “natural” and “smooth” path for ships.

The advantage of this is a more natural path is found and smoothed as a result, it essentially tries to create a smooth path from start to end with speed and dynamic objects in mind. Also, in this example a larger map is used, which is much bigger than our own max map size of 20x20.

On the other hand, this paper requires a map which is quite open and mostly free of claustrophobic conditions, ones that would absolutely occur in our own maps & mazes. If the maps were smaller and had more obstacles it would then take long to solve the path.

**Evolving Sparse Direction Maps for Maze Pathfinding** [3] uses a genetic algorithm to create a path on a 2d grid with obstacles. This is achieved by segmenting the map into slightly large cells which group the actual cells and defines that section with a direction. The agents will then travel in the direction in which the parent cell is pointing towards.

The authors say that if you have a small not to complex map (ours is a maximum of 20x20), we can expect a result in a relatively short amount of time. This paper is also much more specific to requirements needs then the last paper as it considers a map in the same visual layout and the same degrees of freedom as our own. Additionally, with a maximum map of 20x20 it will be able to solve in a small amount of generations, however this may not be practical in real-time. A threaded implementation may be more practical.

On the other hand, the implementation noted that depending on the complexity of the map it can take up to a lot of time. This complex map of 15x15 took over 3 hours to solve on a Pentium 3. This is an older CPU and the implementation would fare much better on today’s CPUs like the one I’m testing on, but this would be nowhere near practical for a real-time pathfinding solution for games, especially for those games that run on a single thread. It states that it took 1220 cycles of the genetic algorithm to solve the 15x15 maze which may be feasible today if the algorithm was only run once at the beginning. Unfortunately, we need the implementation to be practical in a real-time process because the pathfinding algorithm may be called many times in a single frame by many different agents. Finally, they say that this will also not always find the shortest path, much like A\* the algorithm will stop once a path has been found, which may stop if the random generation are unlucky.

From these 2 implementations the problem of runtime or cycles starts to become a problem as boundaries get larger and obstacles become abundant.

Algorithm Choice

I have decided to implement an artificial neural network.

# Implementation and Evaluation

Before the test results I will mention the constants and variables I have used in my test. In my test rig I have used a 4th generation i7 4790K (4.00GHz). The tests will be done at non-overclocked base speed of 4.00GHz on a single thread. I also have 8.00GB of 2300MHz ram installed. The compiler I use is the Microsoft Visual C++ Compiler (SDK Version 10.0.17763.0). Using this compiler, I will provide a result for both debug mode and release mode to represent a development build and commercial build of the software.

The variable in these tests are the maps themselves in several forms. The first pairing is a small map of (10x10) and a large map (100x100) with natural obstacles that would be seen in a game. The next paring is a possible small (10x10) and large (100x100) but have the longest possible path to the solution for that grid size. Finally, I have an very large, possible and impossible map tests at a size of 1000x1000 (1,000,000 nodes). The last case unoptimized is generally unadvised but it should show that both algorithms can work on any sized map.

Mention

* + Memory Processed
  + Memory Needed
  + Time Taken in both Debug and Release Configurations

# Conclusion

* Describe the implementation process in the terms of a games company and how having used the paper has helped for their games development process.

# References

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2. Leigh, R., Shshil, J.L. and Miles, C., 2007. Proceedings of the 2007 IEEE Symposium on Computational Intelligence and Games: Using a Genetic Algorithm to Explore A\*-like Pathfinding Algorithms. Date 1-5 April 2007. Doi: 10.1109/CIG.2007.368081
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