Multi-Robot Path Planning with Due Times

Hanfu Wang and Weidong Chen

Institute of Medical Robotics and Department of Automation,
Shanghai Jiao Tong University

January 16, 2022

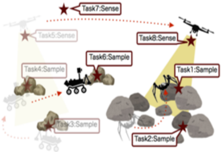
上海交通大學
SHANGHAI JIAO TONG UNIVERSITY

Outline

Introduction: Multi-Robot Path Planning

- multi-robot path planning (MRPP)[1] or multi-agent path finding (MAPF)[2] is an enabling research field for practical deployment of multi-robot systems

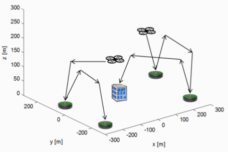
(a)



(b)

(c)

(d)



(e)

[1] Lynne E. Parker. "Multiple Mobile Robot Teams, Path Planning and Motion Coordination in". In: *Encyclopedia of Complexity and Systems Science* (2009), pp. 5783–5800. DOI: 10.1007/978-0-387-30440-3_344.

[2] Roni Stern. "Multi-Agent Path Finding – An Overview". In: *Artificial Intelligence*. Springer International Publishing, 2019, pp. 96–115. DOI: 10.1007/978-3-030-33274-7_6.

Introduction: Solutions

- MRPP or MAPF can be solved by various methodologies:
  - reduction-based (SAT, ILP, AST...)
  - search-based, optimal (CBS, ICBS, M*...)
  - search-based, bounded suboptimal (ECBS, CBS-HWY...)
  - search-based, unbounded suboptimal (HCA*,WHCA*,co-WHCA*...)
  - rule-based (Push&Swap, Push&Rotate, traffic rules...)
  - decoupled (prioritized planning, path coordination...)
  - sensor-based or reactive (ORCA...)
  - learning-based (PRIMAL,PRIMAL2,MAGAT...)
  - ...

Motivation

- in practice, multi-robot systems have to accomplish tasks with due times can be anticipated
- multi-robot path planning with time and distance-based objectives:[3]
  - makespan
  - total travel times
  - maximum distance
  - total distances
- multi-agent path finding with deadline-based objectives:[4]
  - the number of successful agents
- none of existing problem formulations could reflect soft temporal constraints of tasks[5]

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[3] Jingjin Yu and Steven M. LaValle. "Optimal Multirobot Path Planning on Graphs: Complete Algorithms and Effective Heuristics". In: *IEEE Transactions on Robotics* 32.5 (2016), pp. 1163–1177. ISSN: 15523098. DOI: 10.1109/TRO.2016.2593448. arXiv: 1507.03290.

[4] Hang Ma et al. "Multi-agent path finding with deadlines". In: *IJCAI International Joint Conference on Artificial Intelligence* 2018-July (2018), pp. 417–423. ISSN: 10450823.

[5] Ernesto Nunes et al. "A taxonomy for task allocation problems with temporal and ordering constraints". In: *Robotics and Autonomous Systems* 90 (2017), pp. 55–70. ISSN: 09218890. DOI: 10.1016/j.robot.2016.10.008.

Problem Formulation: MRPP-DT

- inputs:
  - underlying graph $G = (V, E)$
  - robot set R composed of n robots
  - start vertices V_s
  - goal vertices V_g
  - due times D
- outputs:
  - n feasible collision-free paths $P = \{p_1, \cdots, p_n\}$
- three due time-related objectives:
  - minimization of maximum lateness L_{max}
  - minimization of total tardiness $\sum_{i=1}^{n} H_i$
  - minimization of total unit penalties $\sum_{i=1}^{n} U_i$

Examples and Problem Analysis

Problem: Multi-Robot Path Planning with Due Times

Given (G, R, V_s, V_g, D) as is described previously, find an optimal solution $P = \{p_1, \cdots, p_n\}$ composed of n feasible collision-free paths for all robots with objective 1, 2, or 3.

Intractrability

The MRPP-DT problem is NP-hard.

Parato Structure

Any two of seven objectives cannot be optimized simultaneously.

Examples

Examples

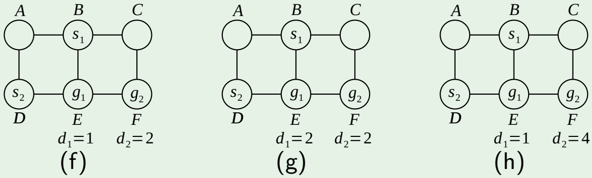
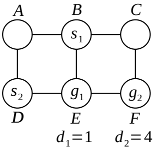
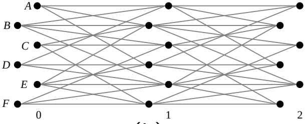


Figure: Three examples with the same start and goal vertices, but different due times. The underlying graph has 6 vertices.

Reduction-based Algorithms



(a)



(b)

$$\min : l_{max}$$

$$\min : nT - \sum_{i=1}^{n} d_i - \sum_{i=1}^{n} \sum_{t=1}^{T} z_i^t y_i^t$$

$$\min : n - \sum_{i=1}^{n} \sum_{e_j \in \delta^-(v_t)} x_{i,j}, v_t \in \mathcal{S}^*$$

(c)

Completeness Theorem

MinMaxLat, MinTotalTard, MinTotalUP are all complete.

Instance Design

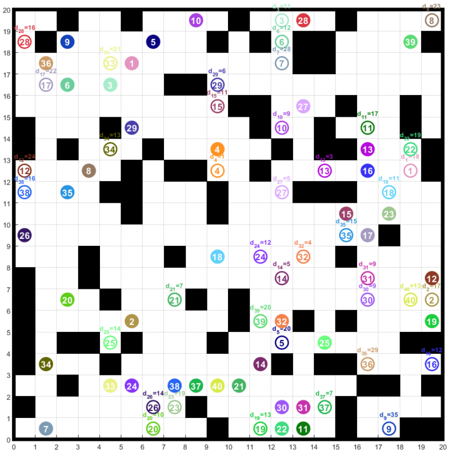


Figure: An MRPP-DT instance with 40 robots on a $20 \times 20 \times 20\%$ grid map.

Results of Objective 1

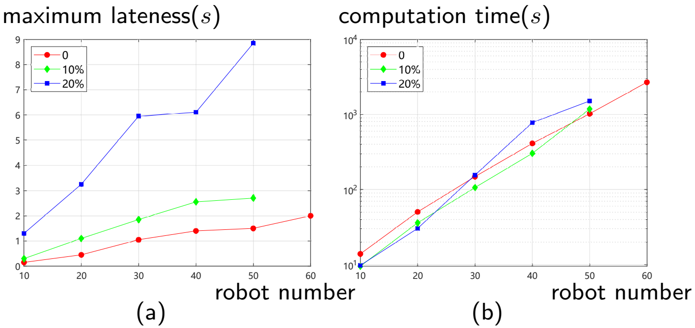


Figure: Performance of MinMaxLat over MRPP-DT instances.

Results of Objective 2

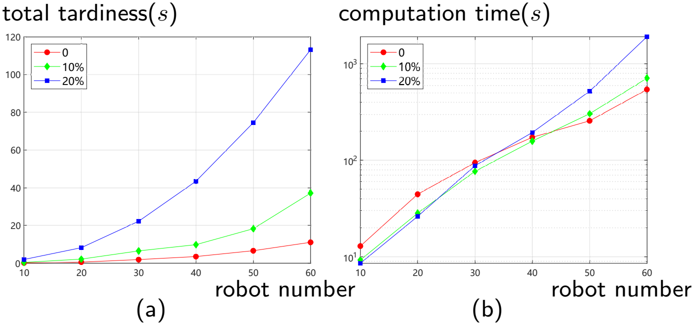


Figure: Performance of MinTotalTard over MRPP-DT instances.

Results of Objective 3

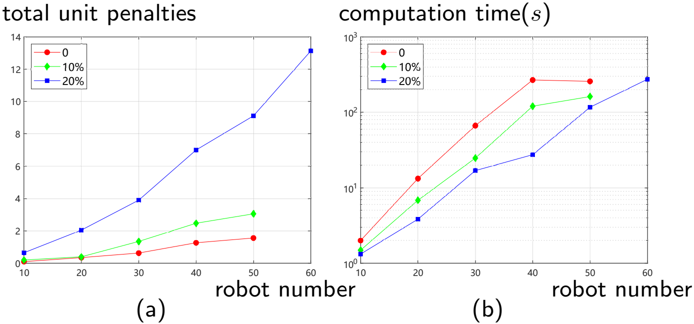


Figure: Performance of MinTotalUP over MRPP-DT instances.

Conclusions and Future Work

- conclusions:
  - MRPP-DT is formulated to address task awareness in path coordination level
  - complete reduction-based algorithms are developed
  - proposed algorithms can solve small-scale problems in allocated time, with good optimality performance
- future work:
  - develop fast algorithms
  - apply related ideas in practical applications, i.e., logistics
  - combined task and path planning

Key References

[1] Lynne E. Parker. "Multiple Mobile Robot Teams, Path Planning and Motion Coordination in". In: *Encyclopedia of Complexity and Systems Science* (2009), pp. 5783–5800. DOI: 10.1007/978-0-387-30440-3_344.

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