TP N° 6: Crowd Simulation Grupo N° 5

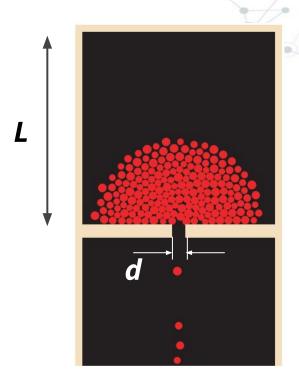


Fundamentos

Sistema Físico

"Comportamiento de una **multitud** intentando evacuar una sala cuadrada."

"La sala posee lado **L**, y una puerta de ancho **d**."



(Social Force Model)

$$\bar{F}_{flow} = \bar{F}_{driven} + \sum \bar{F}_{social} + \sum \bar{F}_{normal} + \sum \bar{F}_{friction}$$

Fuerza de Deseo

$$\bar{F}_{driven} = \frac{m}{\tau} (v_d \hat{n}_0 - \bar{v})$$

• Fuerza Social

$$\bar{F}_{social} = -A e^{\frac{\xi_0}{B}} \hat{n}$$

Fuerza Normal (choque), y de Fricción

$$\bar{F}_{normal} = \left(-k_n \xi_0 - \gamma \xi_1\right) \, \hat{n} \qquad \quad \bar{F}_{friction} = -k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t}$$

$$\bar{F}_{normal} = (-k_n \xi_0 - \gamma \xi_1) \, \hat{n} \qquad \bar{F}_{friction} = -k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} - k_t \, \hat{t} - k_t \, \xi_0 \, \langle r_1^{\Delta}, \hat{t} \rangle \, \hat{t} + k_t \, \hat{t} - k_t \,$$

Dirección normal y tangencial

$$\hat{n} = \frac{r_0^j - r_0^i}{\|r_0^j - r_0^i\|}$$
 $\hat{t} = (-\hat{n}_y, \hat{n}_x)$

Superposición

$$\xi_0 = R_i + R_j - \|r_0^j - r_0^i\|$$

Velocidad de superposición y relativa

$$\xi_1 = \frac{\langle r_0^j - r_0^i, r_1^{\Delta} \rangle}{\|r_0^j - r_0^i\|}$$
 $r_1^{\Delta} = r_1^{i} - r_1^{j}$

$$\bar{F}_{driven} = \frac{m}{\tau} (v_d \hat{n}_0 - \bar{v})$$

Dirección normal hacia el objetivo (target)

$$\hat{n}_0 = \frac{t_0 - r_0^t}{\|\bar{t}_0 - r_0^t\|}$$

 W_{target}

Target ancho

$$w_{target} = d - 2R_{max} - 0.2$$

Target dinámico

$$r_{0,y}^i < 0 \longrightarrow \bar{t}_0 = (r_{0,x}^i, r_{0,y}^i - 1)$$



$$\bar{F}_{social} = -A e^{rac{\xi_0}{B}} \hat{n}$$

- Dirección normal
- Radio de acción (**2.5 m**, máximo)

$$A = 2000 \text{ N}, B = 0.08 \text{ m}, \xi_0 < -2.5 \text{ m} \rightarrow F_{social} < 6 \times 10^{-11}$$



Implementación

Modelo Computacional

- Java 8 SE Release
- JSON

(https://www.json.org/)

Jackson 2.9.5

(https://github.com/FasterXML/jackson)

Ovito

(https://ovito.org/)

Microsoft Excel

(https://products.office.com/en/excel)

Draw.io

(https://www.draw.io/)

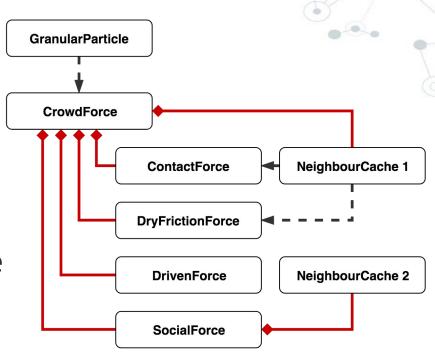
- Reutilización de:
 - Todo el **TP N° 5** !!!
- Integrador Beeman
- Doble caché (cell Index)
- Solo se agregan 2 fuerzas:
 - DrivenForce
 - SocialForce

Campos de Fuerza

(ForceField<T> Interface)

CrowdForce

- DrivenForce
- SocialForce
- ContactForce
- DryFrictionForce



Configuración

(JSON Input)

Paso temporal (10⁻⁴)

$$\Delta t < \sqrt{\frac{m}{100 \, k_n}}$$

- Paper de Vicsek¹ et. al.
- Amortiguación crítica

$$\gamma_{critic} = 2\sqrt{mk_n}$$

```
: "res/data/output",
"output"
"delta"
                     : "0.0001",
"time"
                     : "120.0".
"fps"
                     : "50",
"playbackSpeed"
                     : "1.0",
"samplesPerSecond"
                     : "200",
"integrator"
                     : "BeemanIntegrator",
"reportEnergy"
                     : "false",
"reportTime"
                     : "true",
"radius"
                     : ["0.25", "0.29"].
"mass"
                     : "80.0",
"elasticNormal"
                     : "1.2E+5".
"elasticTangent"
                     : "2.4E+5",
"viscousDamping"
                     : "6196.773354",
"siloDamping"
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"a"
                     : "2000.0",
"b"
                     : "0.08",
"tau"
                     : "0.5",
"desiredSpeed"
                     : "5.0",
                     : "2.5",
"breakRange"
                     : ["10.0", "0.0"],
"target"
                     : "0.42",
"targetWidth"
"generator"
                     : "73604268647601935",
"n"
                     : "200",
                     : "20.0",
"height"
                     : "20.0",
"width"
"drain"
                     : "1.2",
"window"
                     : "5.0",
                     : "0.01"
"flowRate"
```

^{1 &}quot;Simulating Dynamical Features of Escape Panic". Dirk Helbing, Illés Farkas and Tamás Vicsek. Nature, Vol. 407. 28th September, 2000. Macmillan Magazine.

Formato de Archivos

(Output)

- Formato *.static, propiedades estáticas del sistema:
 <radius> <mass>
- Formato *.state, para el estado del sistema (propiedades dinámicas):
 <x> <y> <vx> <vy></x>
- Formato *.pressure, para almacenar la presión:
 <pressure>
- Formato *.xyz (para Ovito):

<time>

<x> <y> <radius> <speed> <pressure>



Consideraciones

• Se colorean las partículas según la **presión**:

$$P = \frac{1}{2\pi R_i} \left\| \sum_{i} \bar{F}_{normal} + \bar{F}_{social} \right\|$$

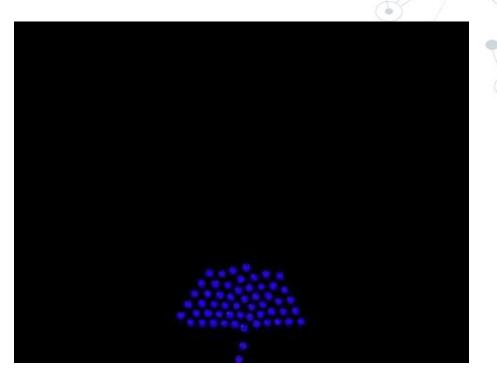
- La fuerza social **no aplica contra las paredes**, como en *Vicsek et. al.*
- No hay reingreso de partículas.
- Todos los *peatones* poseen la misma masa (**80 kg**).
- Se utiliza sliding-window para computar la evolución del caudal (ventana de 5 s y sliding de 0.01 s).
- El valor promediado en la ventana (*Tn, Tn+1*), se asigna a *Tn+1*.

Sliding-window

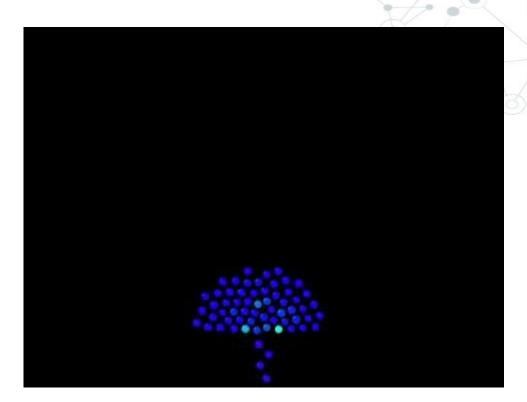
(Cálculo del Caudal)

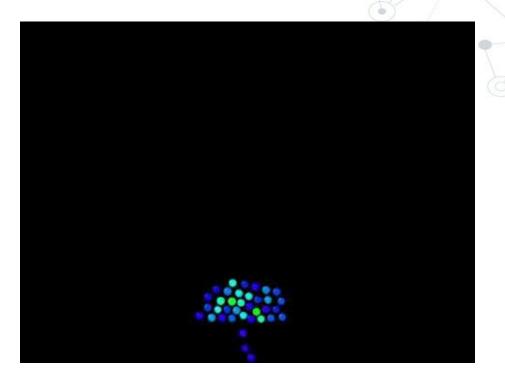
- Sea E = T(0), ..., T(n) una lista de tiempos de egreso.
- Sea **W** el ancho de la ventana.
- Sea **S** el sliding.
- Sea T el tiempo máximo muestreado.
- Sea Q(e) = e/W el caudal, siendo e los egresos en el tiempo t.
- Aplicar el siguiente algoritmo:
 - 1. Sea **k** entero entre **0** y **ceil((T W)/S)** (ambos, inclusive).
 - 2. Sea $\Delta t = kS$ y $t = W + \Delta t$.
 - 3. Definir $e = \#\{t' en E \mid \Delta t \le t' < t\}$.
 - 4. Definir el caudal en el tiempo **t** como **Q(e)**.
 - 5. Repetir para el siguiente k.

```
{
...
"time" : "180",
"n" : "100",
"deltat" : "0.002",
"desiredSpeed" : "0.5",
}
```

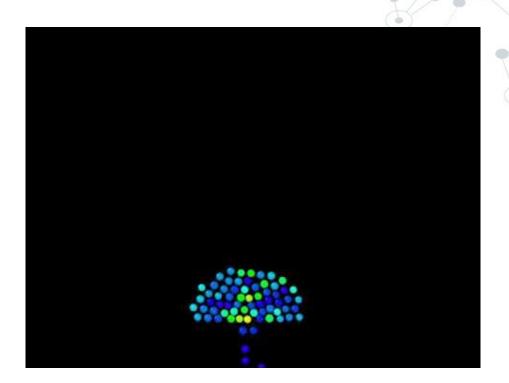


```
{
...
"time" : "75",
"n" : "100",
"deltat" : "0.0005",
"desiredSpeed" : "1.0",
}
```

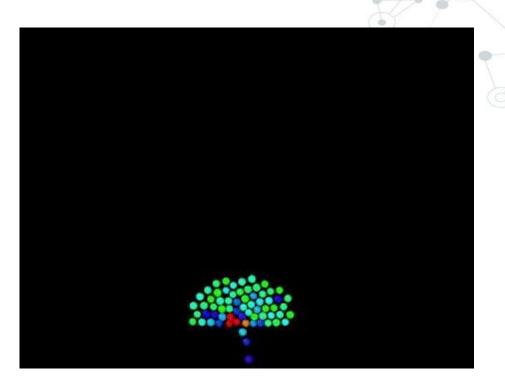




```
{
...
"time" : "30",
"n" : "100",
"deltat" : "0.0001",
"desiredSpeed" : "3.0",
...
}
```



```
"time" : "80",
  "n" : "100",
  "deltat" : "0.0005",
  "desiredSpeed" : "4.0",
}
```

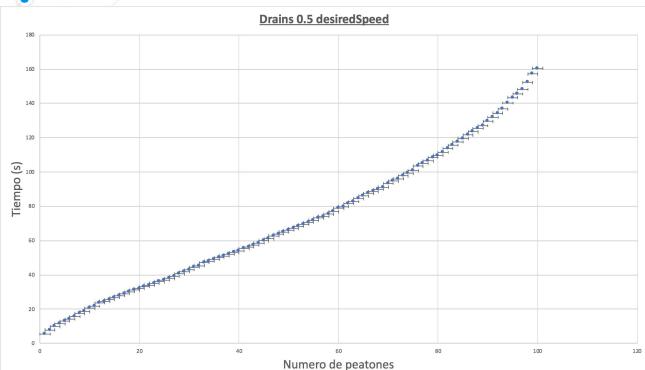


```
{
...
"time" : "80",
"n" : "100",
"deltat" : "0.0005",
"desiredSpeed" : "4.0",
"A" : "0",
...
}
```



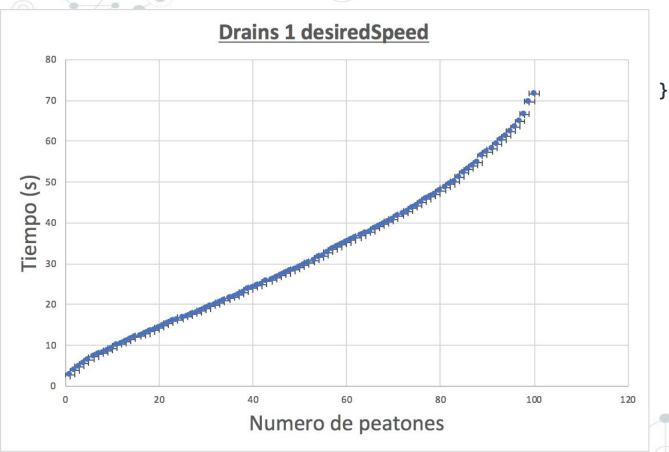
Resultados

<u>Tiempo en f. Del número de peatones</u>



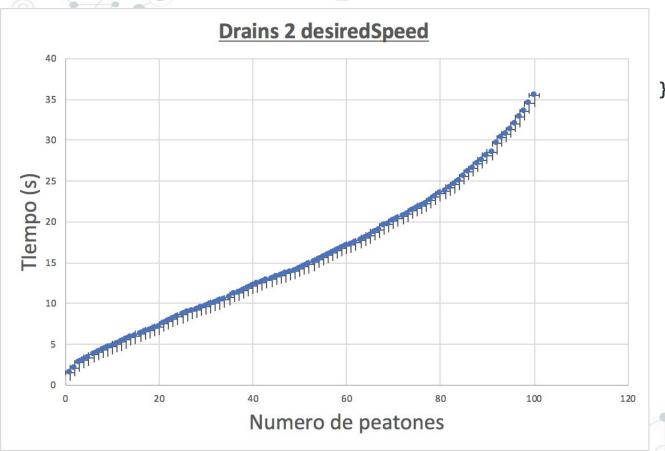
"time" : "180",
"n" : "100",
"deltat" : "0.002",
"desiredSpeed" : "0.5",

Tiempo en f. Del número de peatones



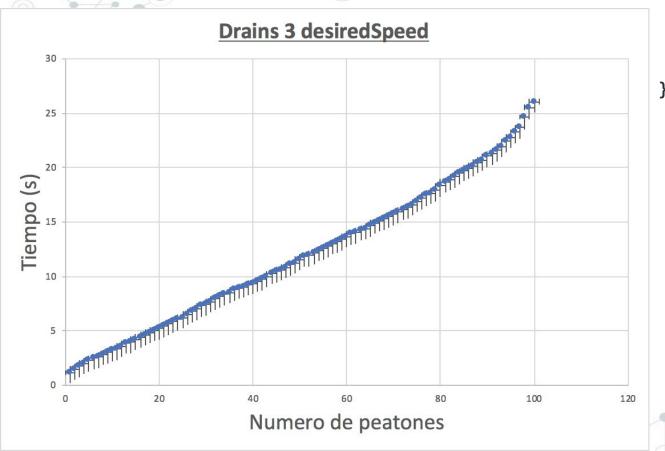
"time" : "75",
"n" : "100",
"deltat" : "0.0005",
"desiredSpeed" : "1.0",

Trempo en f. Del número de peatones



"time" : "40",
"n" : "100",
"deltat" : "0.0003",
"desiredSpeed" : "2.0",

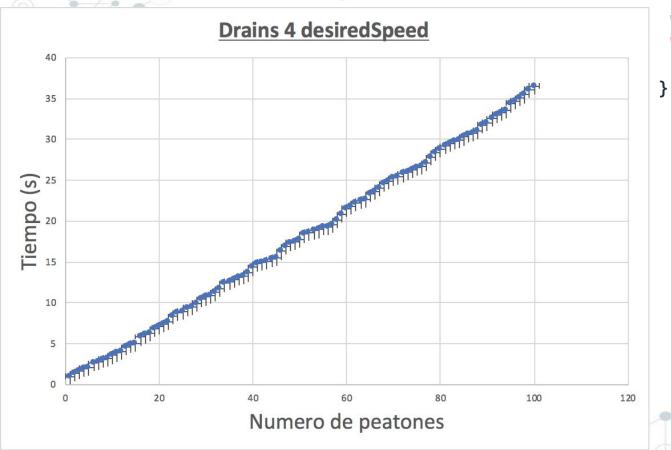
Trempo en f. Del número de peatones



"time" : "30",
"n" : "100",
"deltat" : "0.0001",
"desiredSpeed" : "3.0",

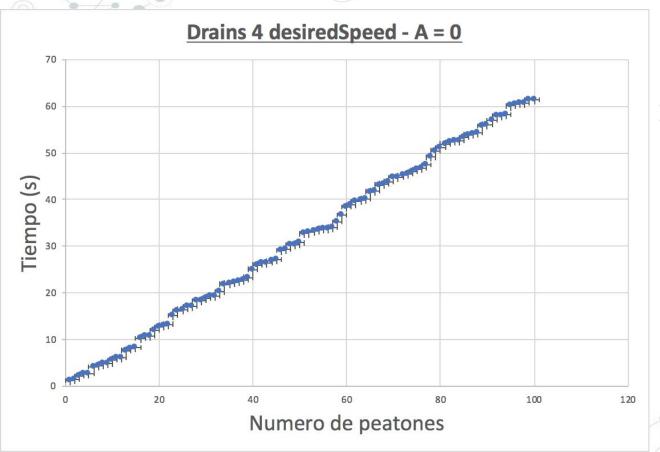
26

Trempo en f. Del número de peatones

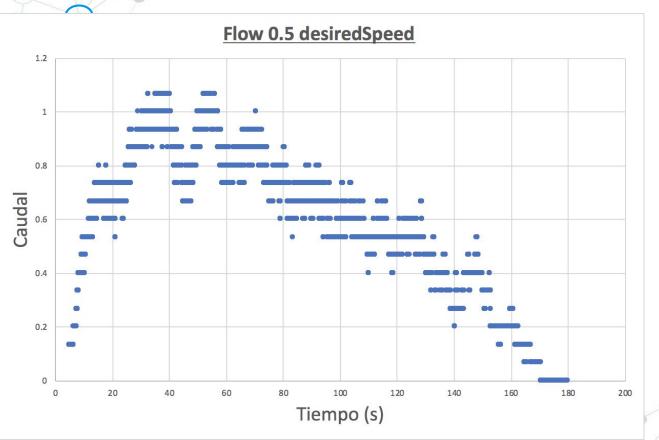


"time" : "80",
"n" : "100",
"deltat" : "0.0005",
"desiredSpeed" : "4.0",

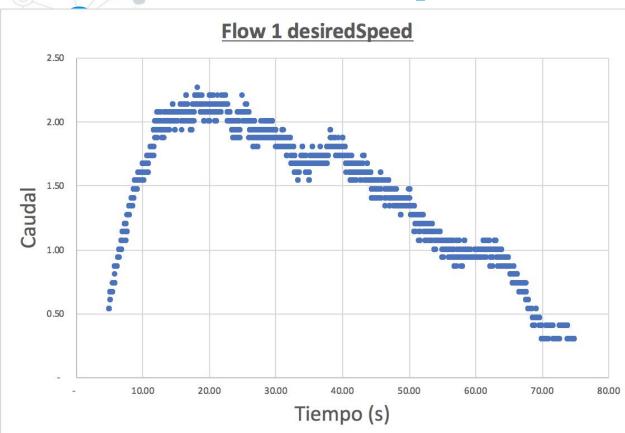
Tiempo en f. Del número de peatones



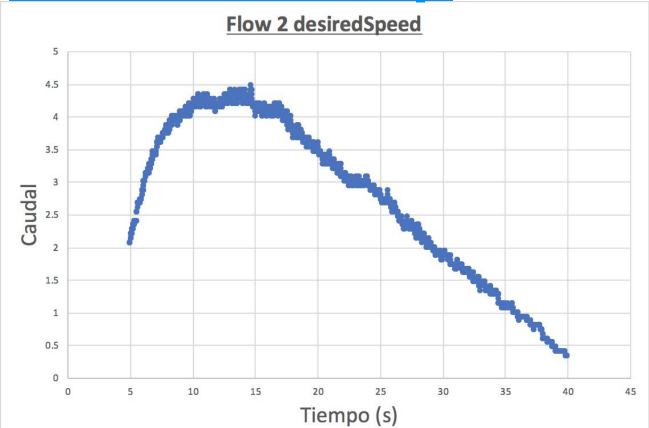
"time" : "80",
"n" : "100",
"deltat" : "0.0005",
"desiredSpeed" : "4.0",
"A" : "0",



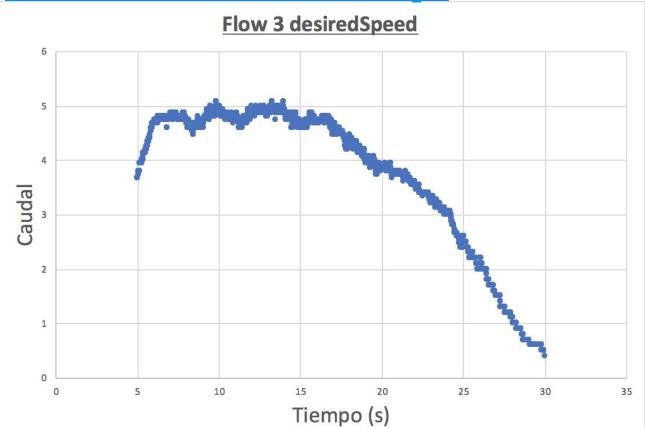
"time" : "180",
"n" : "100",
"deltat" : "0.002",
"desiredSpeed" : "0.5",



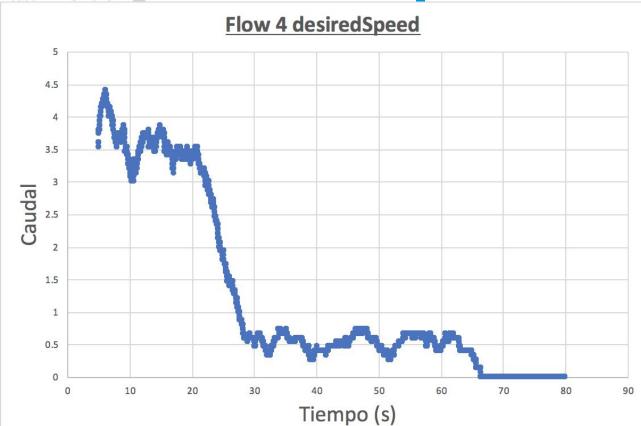
"time" : "75",
 "n" : "100",
 "deltat" : "0.0005",
 "desiredSpeed" : "1.0",
}



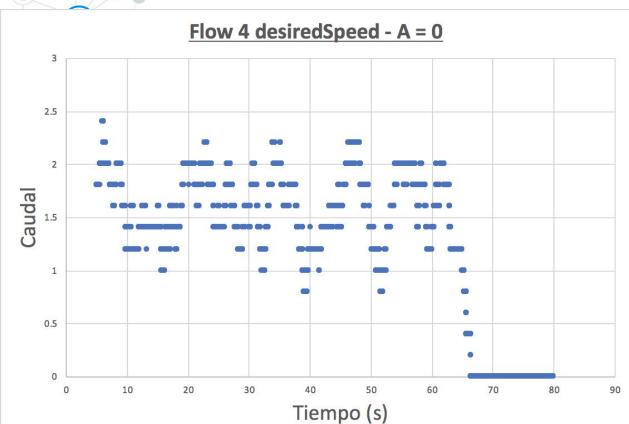
"time" : "40",
"n" : "100",
"deltat" : "0.0003",
"desiredSpeed" : "2.0",



"time" : "30",
"n" : "100",
"deltat" : "0.0001",
"desiredSpeed" : "3.0",
...



"time" : "80",
"n" : "100",
"deltat" : "0.0005",
"desiredSpeed" : "4.0",



```
"time" : "80",
"n" : "100",
"deltat" : "0.0005",
"desiredSpeed" : "4.0",
"A" : "0",
```

Tiempo de evacuación

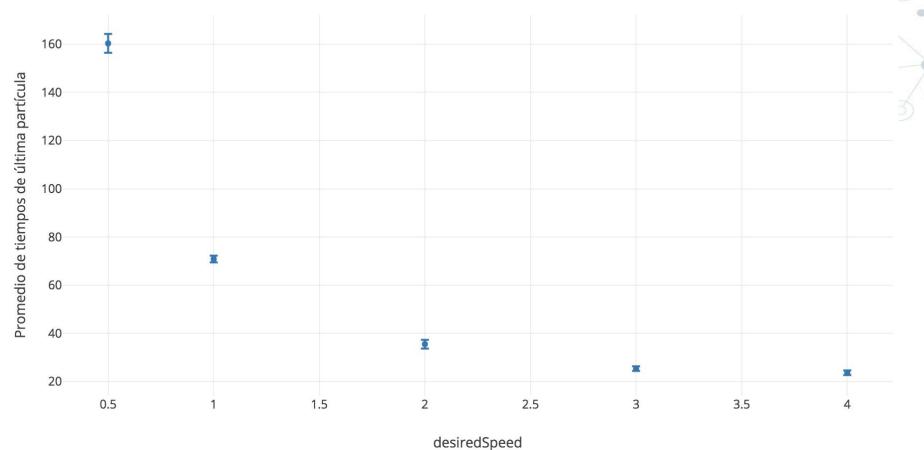
deltat (s)	<u>Generator</u>	<u>N</u>	desiredSpeed (m/s)	Total time (s)	Tiempo de última partícula (s)	Promedio de tiempos de última partícula
						•
	12304268647601935				22.76	ė
0.0005	73604261247601935	100	4	30	23.23	23.66
	73604268647601935				25.01	
	12304268647601935				26.05	
0.0001	73604261247601935	100	3	30	26.05	25.37
	73604268647601935				24.02	

Tiempo de evacuación

deltat	Generator	N	desiredSpeed	Total time	Tiempo de última partícula	Promedio de tiempos de última partícula
	12304268647601935				33.04	••••
0.0003	73604261247601935	100	2	40	36.22	35.53
	73604268647601935				37.33	
	12304268647601935				72.68	
0.0005	73604261247601935	100	1	75	70.76	70.87
	73604268647601935				69.19	
	12304268647601935				165.44	
0.002	73604261247601935	100	0.5	180	155.89	160.37
2 3	73604268647601935				159.8	

Tiempo de evacuación

Tiempo de evacuación



Conclusiones



Conclusiones

- A mayor desiredSpeed, menor es el tiempo de evacuación.
- A = 0 hace que aumente el tiempo de evacuación.

Gracias! Grupo N° 5

