

A decorative graphic on the left side of the slide consisting of two overlapping parallelograms. The front one is blue and the back one is a light green color. They are positioned diagonally, with the blue one in front of the green one.

# Fast LTL pathfinding in partially known environments

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# Purpose

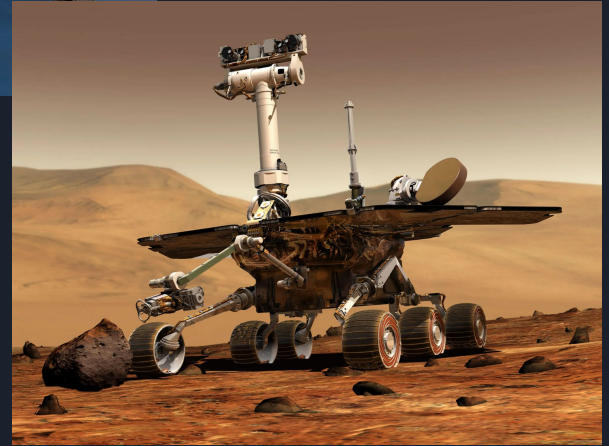
## Defense Sector

- Tasked Agent
- Risky Combat Zones



## Space Sector

- Detect and avoid risk
- Satellite imagery



# Abstract

## Agent

- Must complete task
- Must not crash

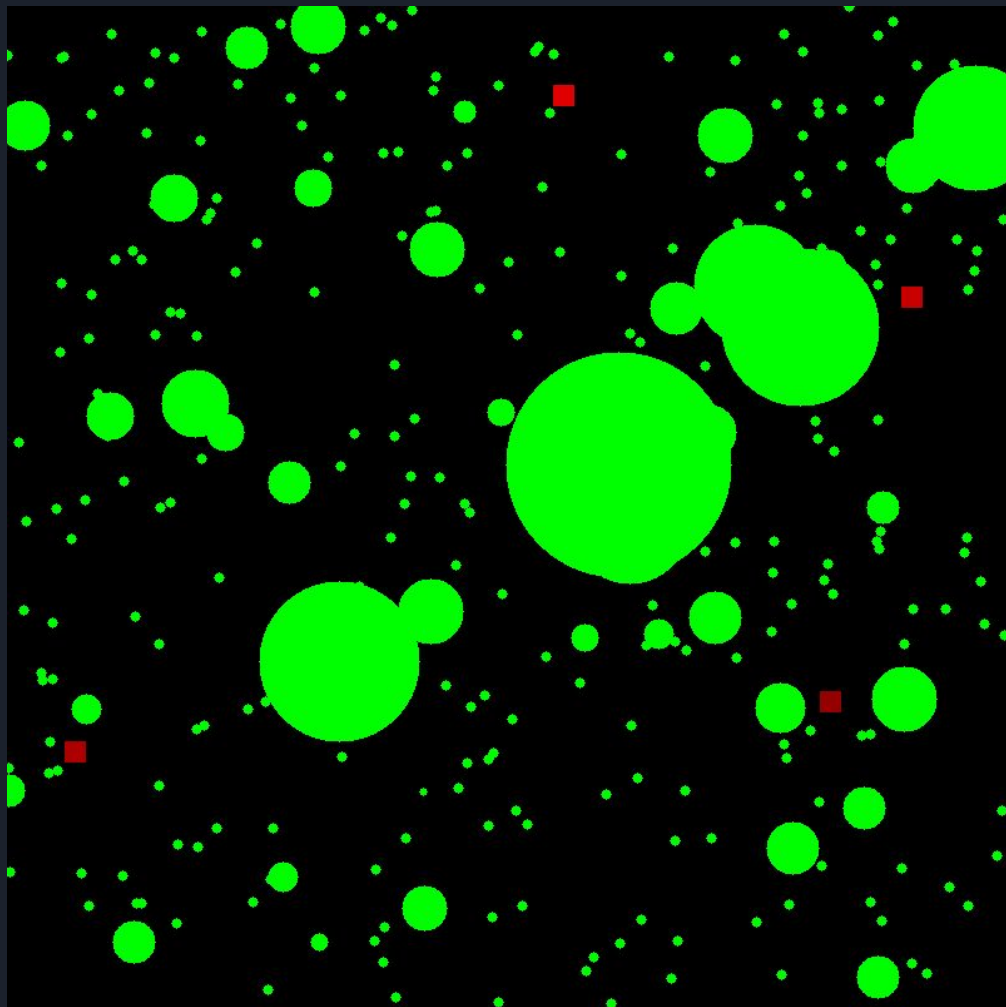
## Risky Environment





# Environment

- Risky objects (green)
  - Warhead craters
  - Debris
- LTL targets
  - Pickup areas
  - Temporary bases
  - Downed personnel
  - Downed tanks
  - Drilling sites



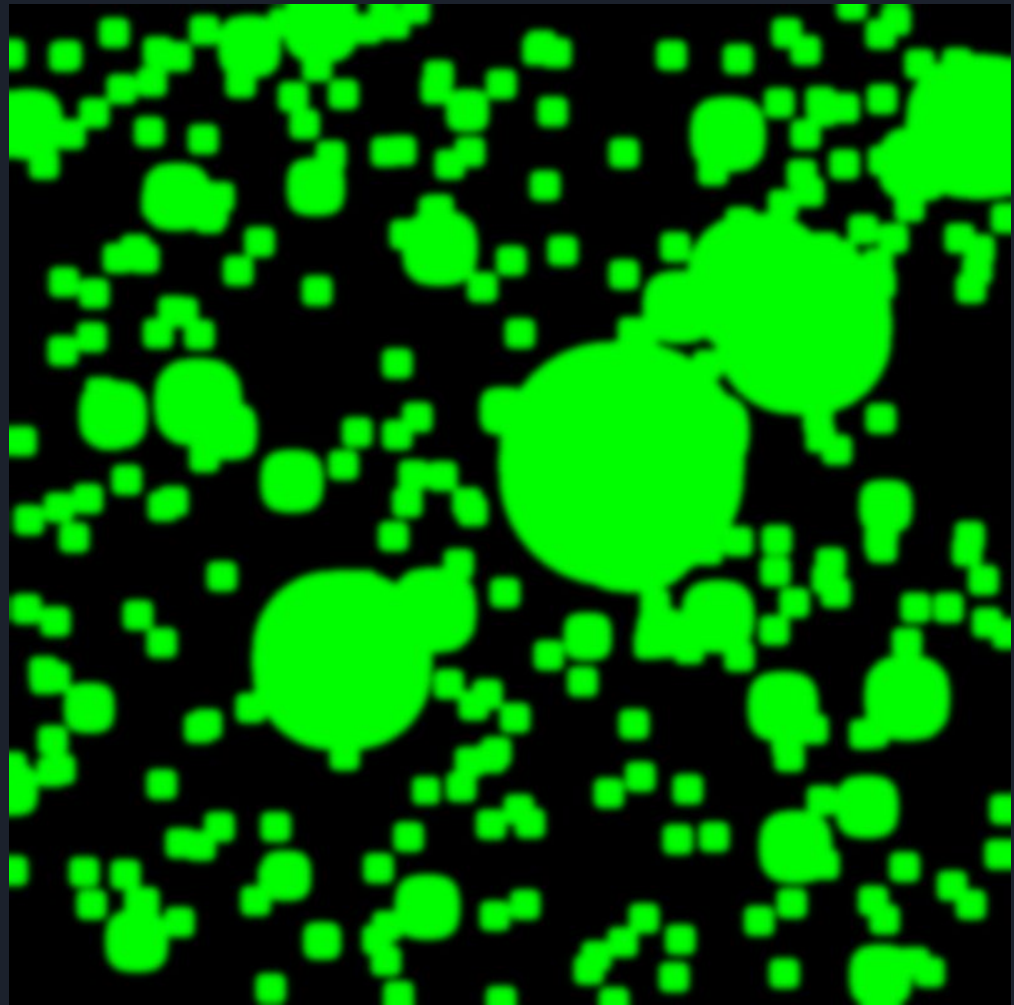


# Satellite Imagery

In the real world, satellite imagery isn't at the best resolution

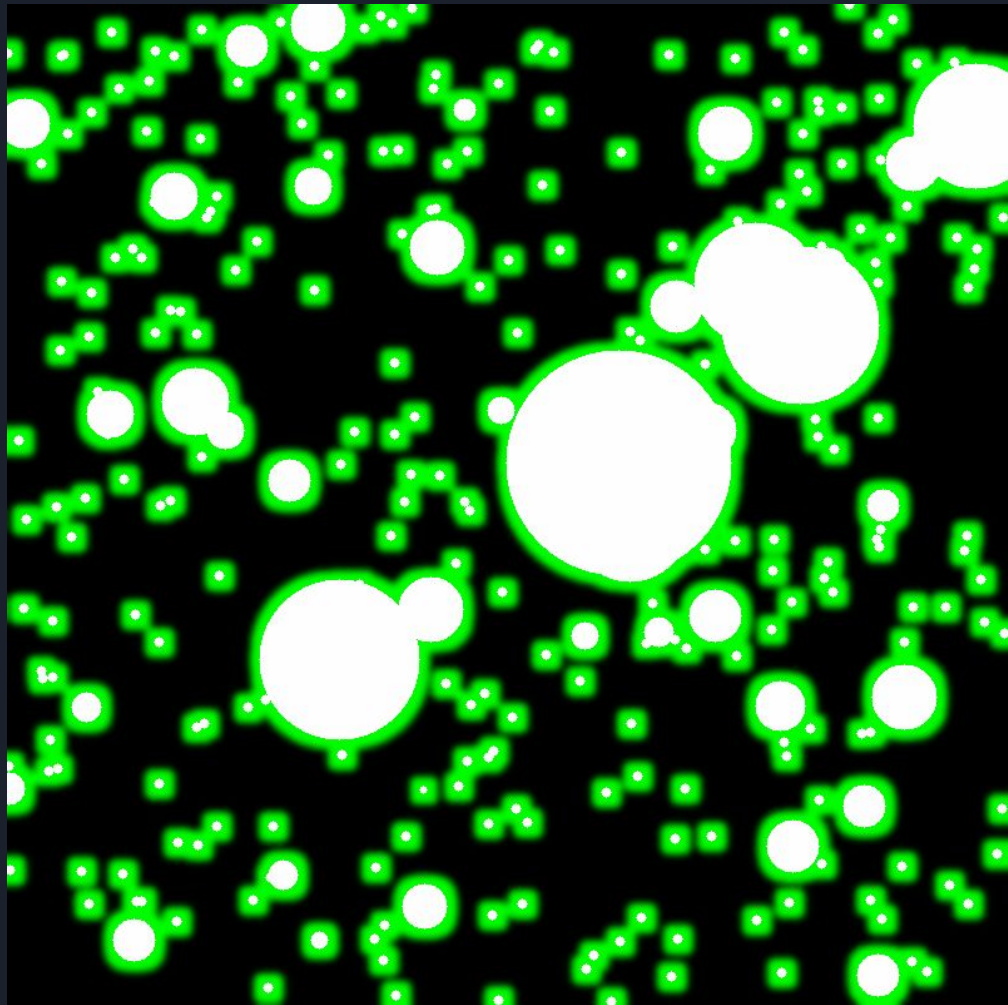
Risk must be assumed surrounding objects

Objects may have been moved by environment, other agents, or antagonists





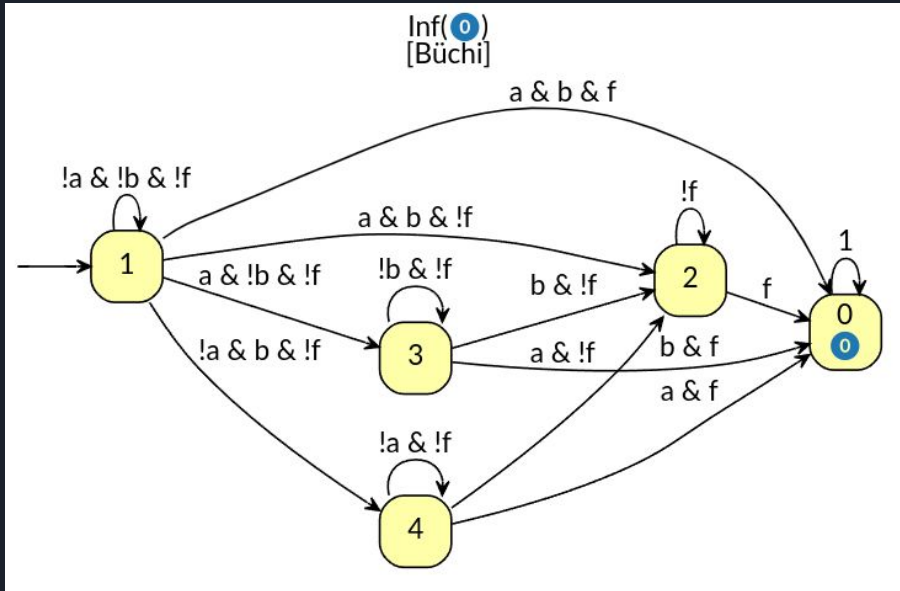
# Satellite Imagery





# Task - Linear Temporal Logic

$Ff \ \& \ (!f \ U \ a) \ \& \ (!f \ U \ b)$



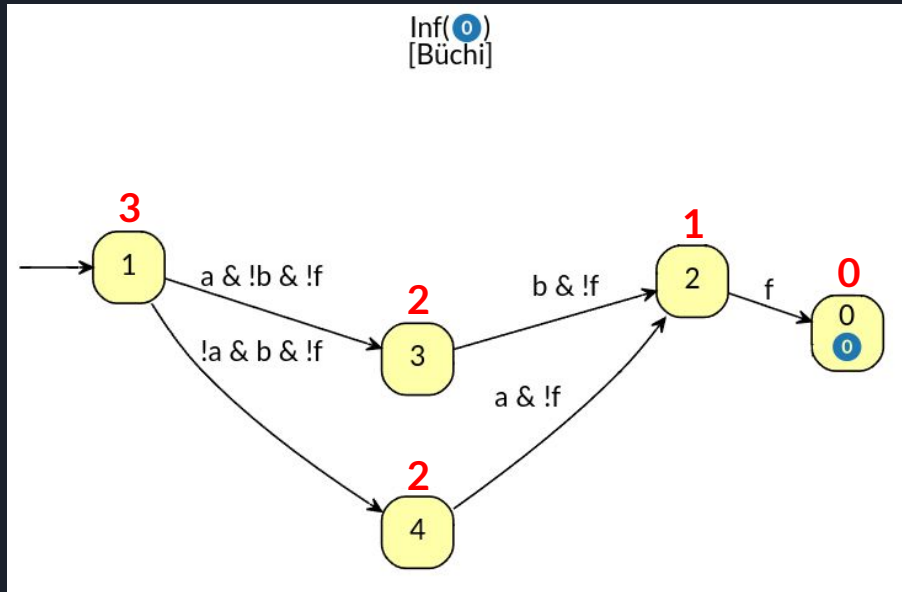
f, a, b are axioms

Can represent

- A physical location
- A intrinsic value
- A extrinsic value

# LTL pathfinding

$Ff \ \& \ (!f \ U \ a) \ \& \ (!f \ U \ b)$



Heuristic Function

- Distance to accepting state

Multiple transition axioms are ignored in the slides for brevity

Better h-functions exist, which will be discussed later as its not programmatically finished



# Pathfinding

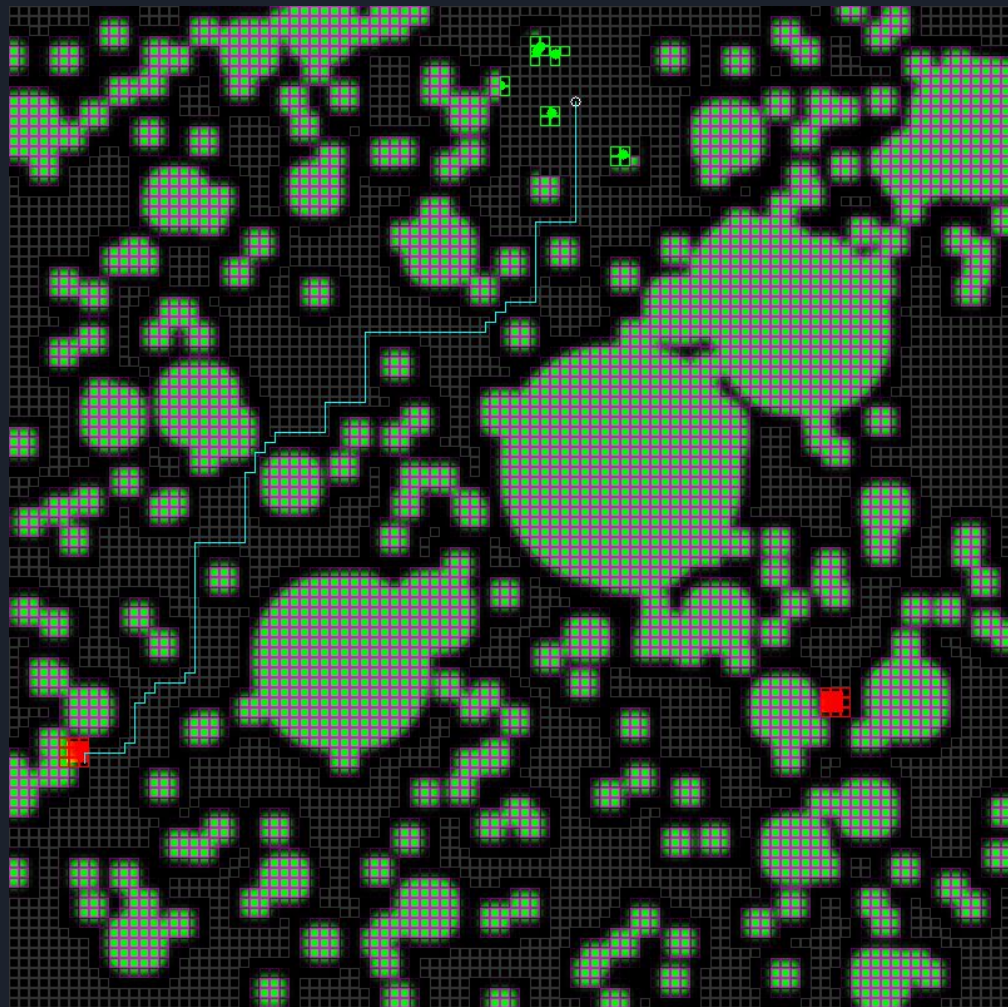
a and b sites are possible

Both sites have equal LTL hfunc weight

Algo will choose one with shortest and least risky phys path

WIP: max cumulative risk

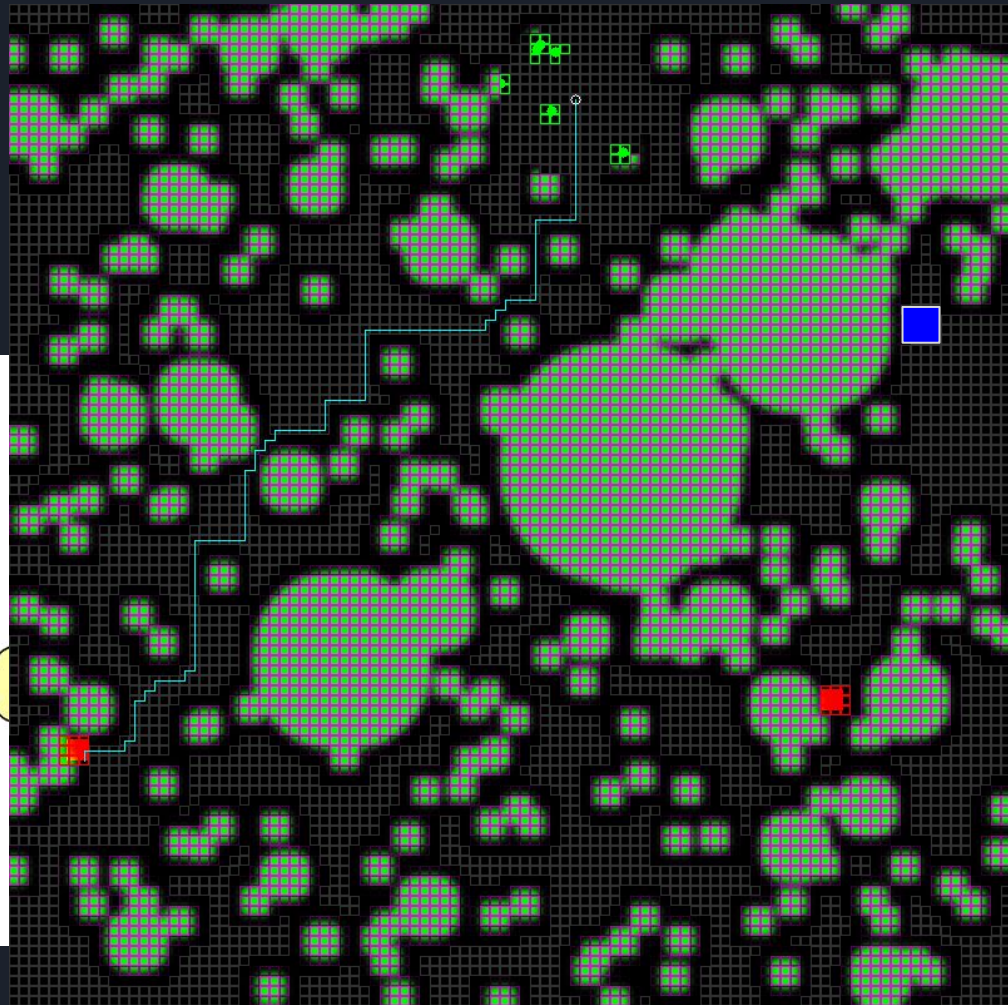
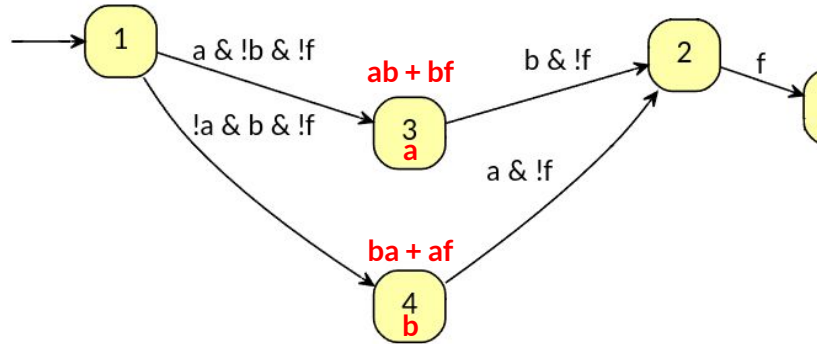
WIP: max absolute risk



# Pathfinding

$Ff \ \& \ (!f \ U \ a) \ \& \ (!f \ U \ b)$

Inf(0)  
[Büchi]

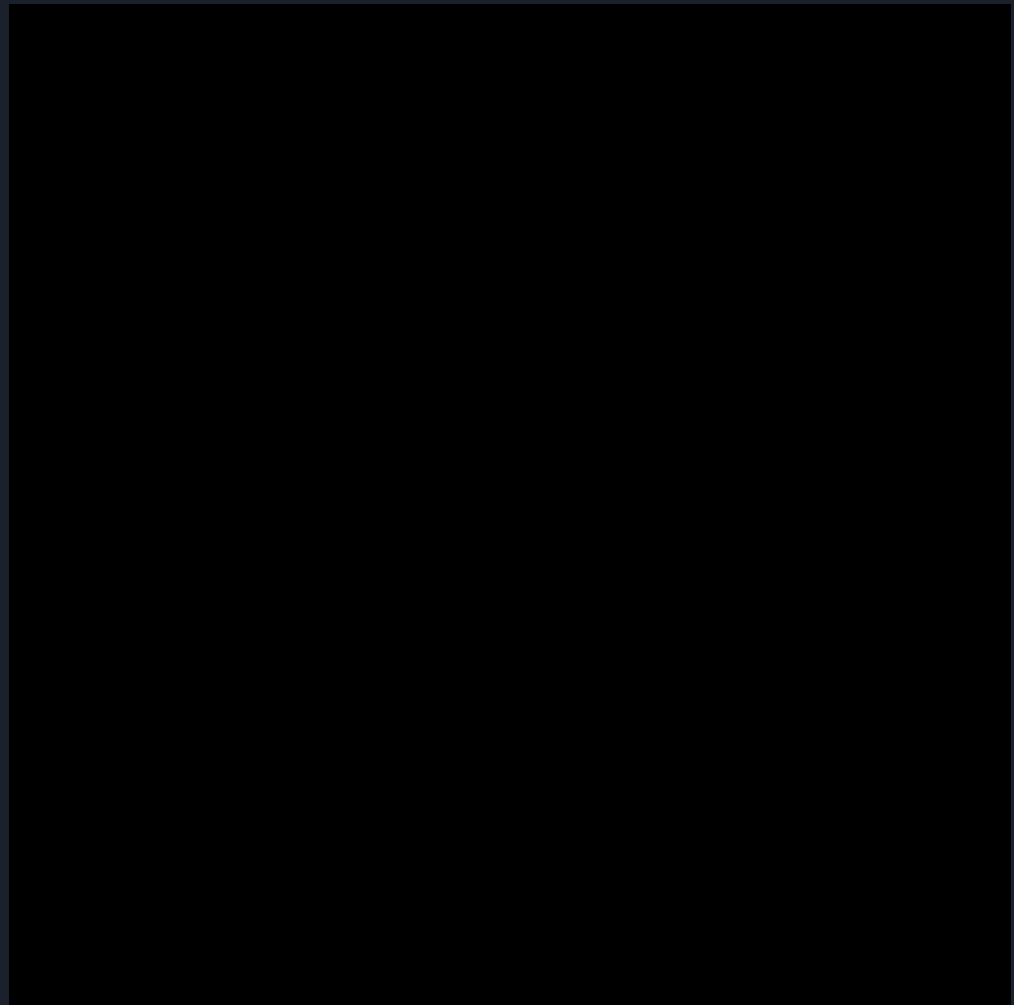




# Pathfinding

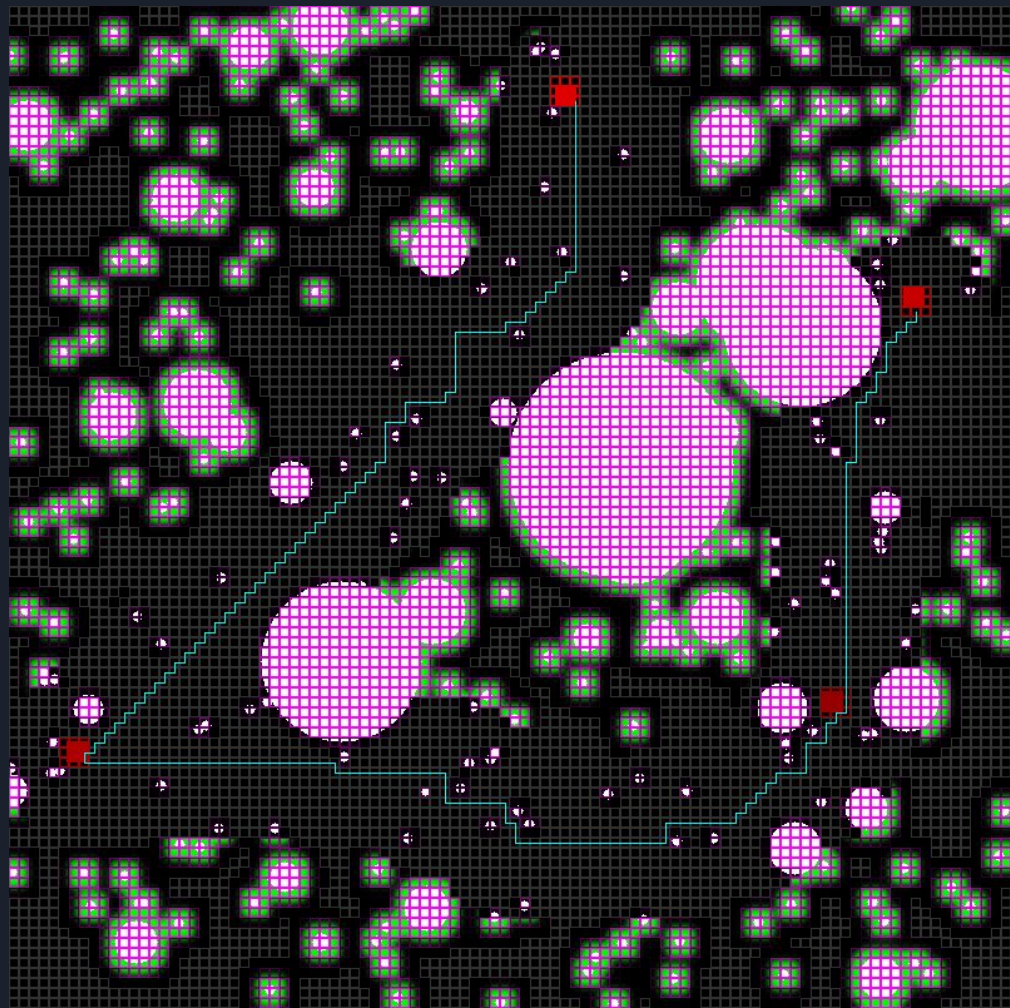
Dynamic Risk

Partial A\* (WIP)





# Pathfinding

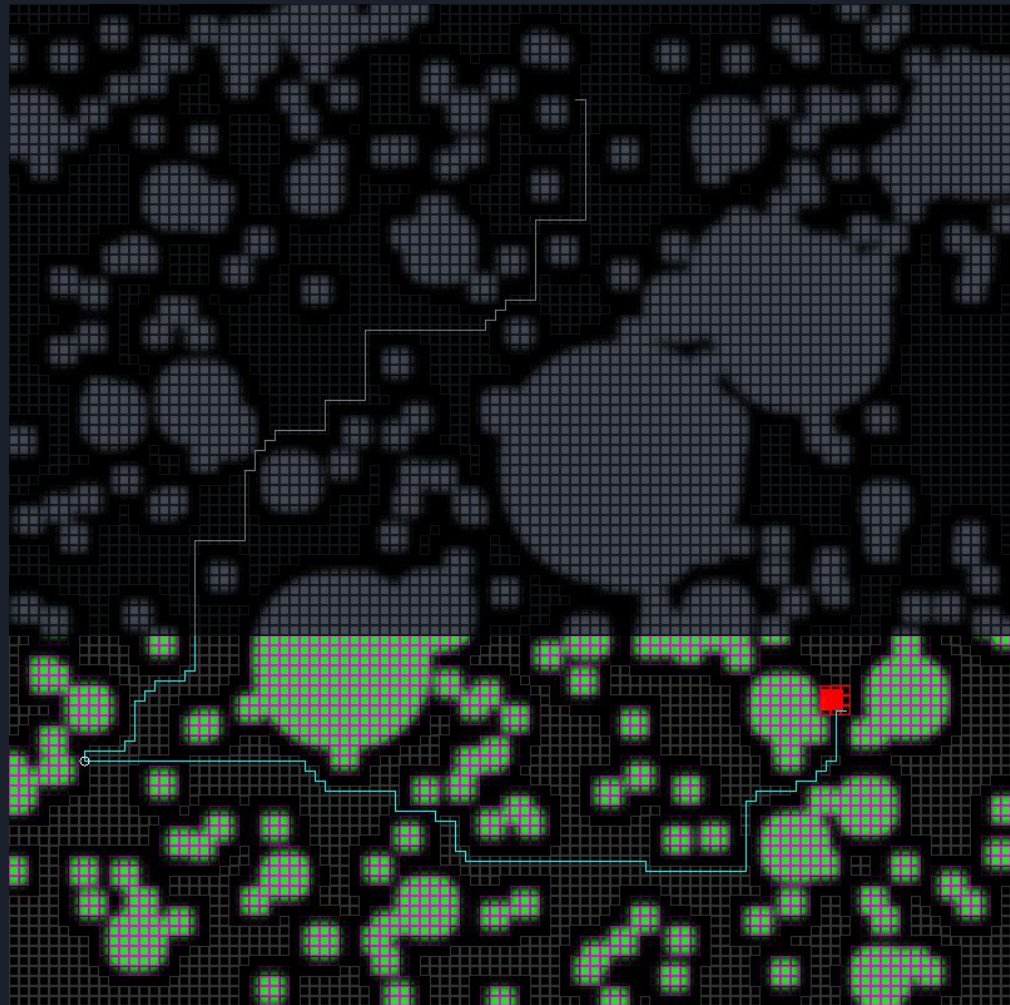




# Pathfinding

no risk updates  
full astar

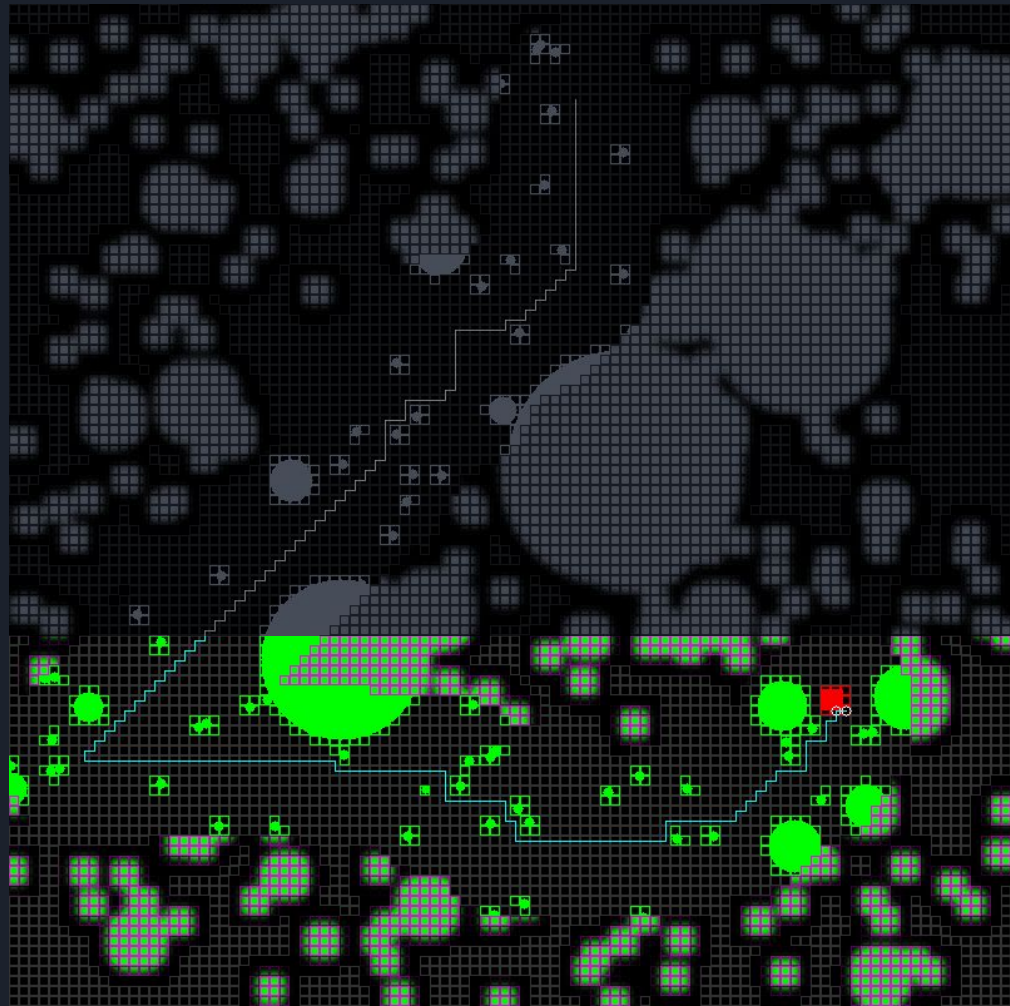
len: 104



# Pathfinding

with risk updates  
partial astar

len: 98

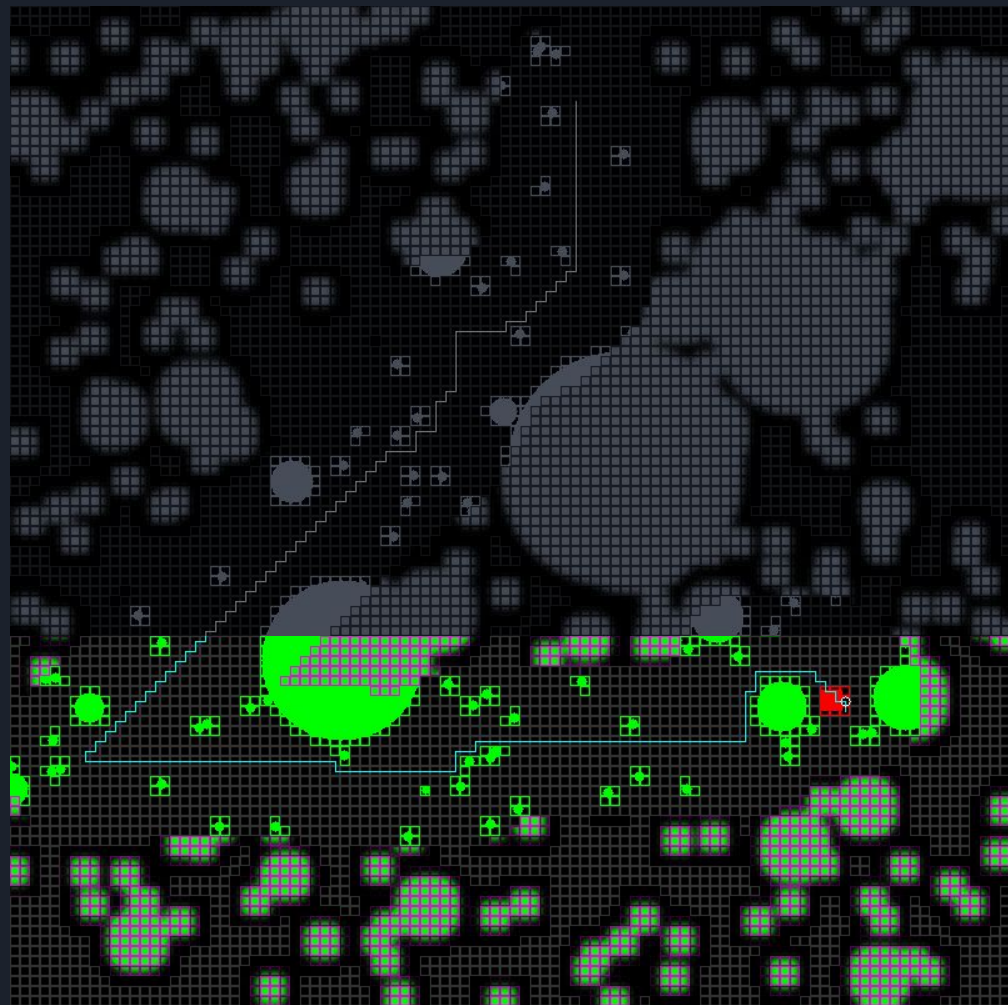




# Pathfinding

with risk updates  
full astar

len: 90

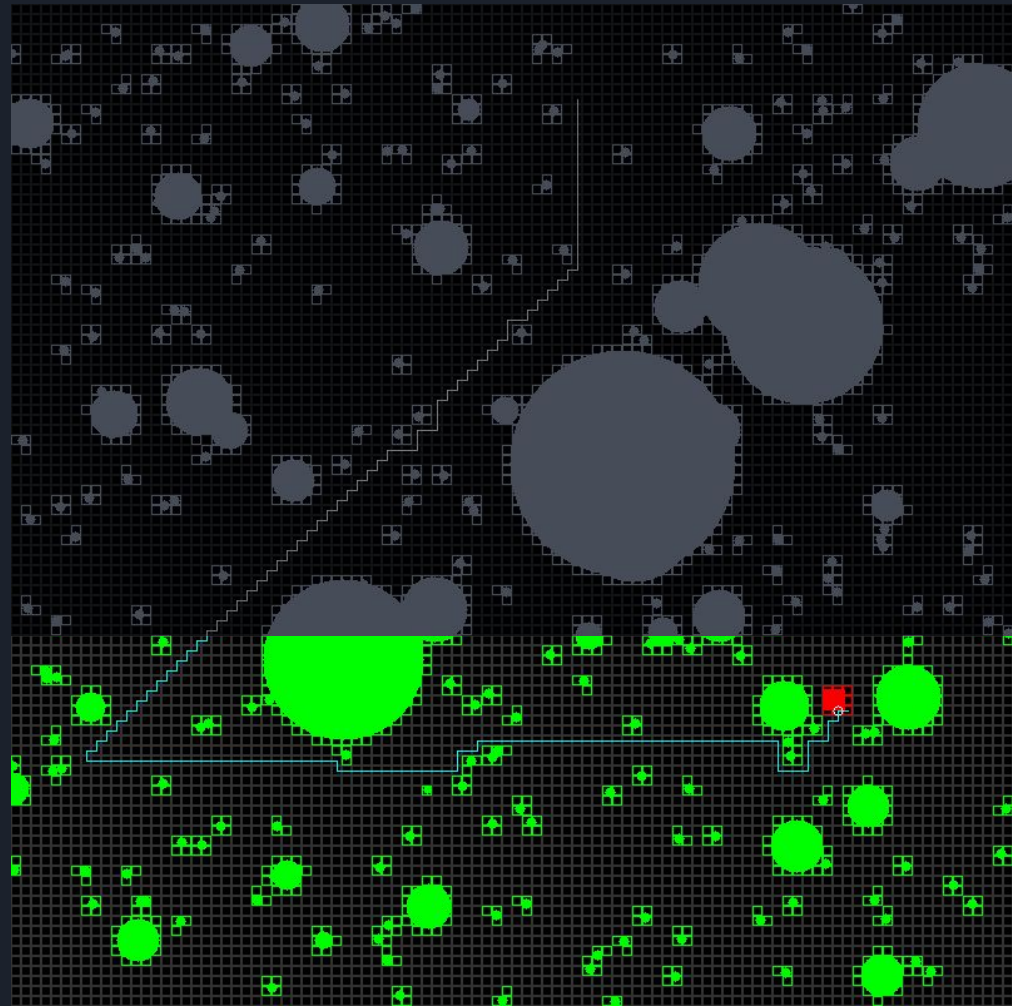




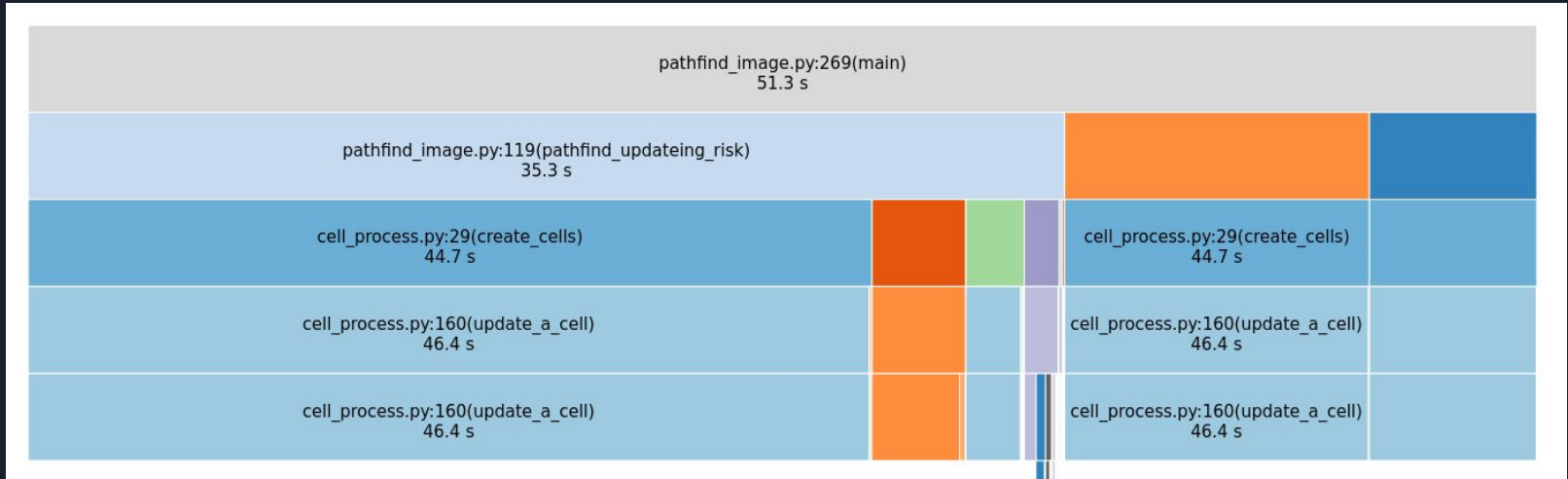
# Pathfinding

no risk  
full astar

len: 90



# Timing



Timings on image are correct but misleading

Entire Script - 51.7s

Final Image Creation (debugging) - 10.4s

Algo - 41.3s

- Pre-processing - 35.8s
- Updating risk - 5.1s
- Astar - 1.2s

# Timing





# Timing



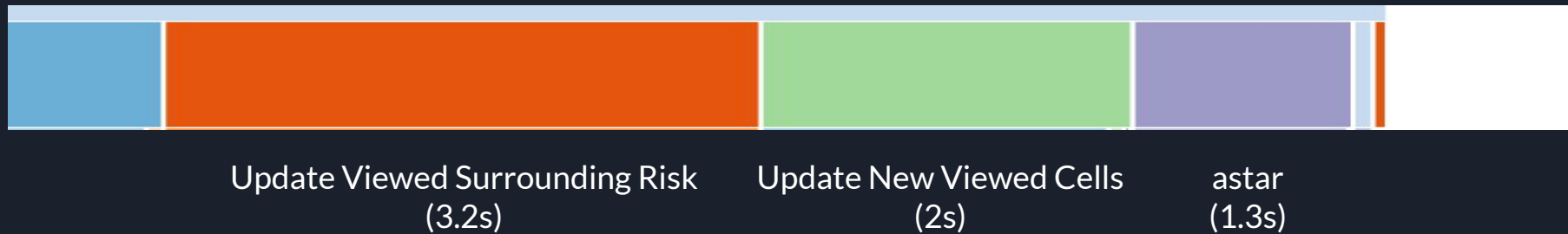
pathfind\_image.py:119(pathfind\_updateing\_risk)  
35.3 s

cell\_process.py:29(create\_cells)  
44.7 s

Extract Cells From  
Satellite Image



# Timing





# Questions?

Constructive Criticism?