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CS 470: BZRFlags Tutorial

Sep 17, 2013

**Really Dumb Agent**

My really dumb agent uses a function call to tick as a counter. Every time tick is called it treats this as if a tenth of a second has transpired. For 80 ticks ~8second the tank will simply plow forward as fast as possible. The for another approximate 8 seconds the tank will slow to half speed and begin turning at full speed. Then the process repeats.

The whole time, however, the tank picks a random number between 0 and 1, if that number is less than .5 it fires its cannon.

~The complete source code is found at the end of this document.

**Potential Fields Implementation and Description**

* Attractive Fields (Write Up and Implementation) Why and How

The attractive fields work by finding the distance and angle that any given x, y position is from a single goal. And return a change in x and a change in y that will bring the given x, y position closer to it.

The magnitude of this change in x and y is governed by two parameters: *radius* and *seek*. Radius governs how big the object actually is, where seek describes an outer parameter of the goal at which an object should slow down. I chose a radius of 1.5 that kept the tanks at full throttle as long as possible until he was almost right on top of the flag, and a seek distance of 30.0 which barely slowed the tanks down as they approached.

I used attractive fields in my implementation to direct tanks to both capture an enemy’s flag and return it back to base. This code is found in the function *def genAnAttractiveField(x, y, goal)* below.

* Repulsive Fields (Write Up and Implementation) Why and How

The simple repulsive field works very similar to an attractive field except that instead of pulling an object closer it drives an object away. This is done by following the exact same process as attractive fields and then simply switching the signs on the changes in x and y.

The meaning of radius and seek are also different in repulsive fields. Radius in this case means to get away as fast as you can, where in attraction it means to stop you have arrived. Seek in this case means the radius around the obstacle for which the repulsion is actually felt. In our game all obstacles are rectangles, so I choose my radius to be the bounding radius of each rectangle. In other words, it was the smallest radius for which the entire rectangle was contained. I also picked a fairly large seek of 60 to help keep any tanks from getting stuck on corners.

I used repulsive forces in my implementation to drive tanks away from obstacles that got in between them and their goals. This code is found in a modified way in the function *def generateAnRepulsiveField(x,y, obsticle, makeItTangent=False, goal=None)* below.

* Tangential Fields (Write Up and Implementation) Why and How

A tangential field is a field that pushes at a 90 angle from a repulsive field.

I used tangential fields in my implementation to help prevent tanks from getting stuck in the world. The tangential field would guild a tank around an obstacle. Without these fields there would be a lot of holes in the field map where attractive fields and repulsive field would simply just cancel each other out. I calculated tangential fields by calling the repulsive field function (def generateAnRepulsiveField(x,y, obsticle, makeItTangent=False, goal=None)) with the makeItTangent variable set to True.

* Tuning Process
  + Size of Radius and Seek

These variables were simple to tweak. Simple took a guess and then printed the potential fields. When the fields looked about right that was it. However, toward the end of the project I found that there was one special case where a tank could get trapped going in a circle on the corner of an obstacle. This led me to increase the repulsive field radius as to slow the tank down before it got right in on the corner.

* + Constants b and alpha

These constants were harder to figure out. After looking at it, I came to the conclusion that they should be 1/seek. This allowed the change in x and the change in y to settle more frequently with values between 0 and 1 with the seek field.

* + Intelligent Tangential Fields  
    Another place of entrapment for my tanks was approaching an obstacle and having it tell the tank to go the long way around. This caused the tank to end up in an infinite circle. So I modified my tangential code to intelligently direct the tank around an obstacle in the direction closest to its goal.

|  |  |
| --- | --- |
| Attractive Fields with Goal Modification  Macintosh HD:Users:clm:Desktop:BYU-FALL-2013:CS470-AI:PotentialFieldsLab:Screenshot from 2013-09-28 16&%19&%03.png | Repulsive Fields  Macintosh HD:Users:clm:Desktop:BYU-FALL-2013:CS470-AI:PotentialFieldsLab:Screenshot from 2013-09-28 17&%19&%48.png |
| Tangential Fields  Macintosh HD:Users:clm:Desktop:BYU-FALL-2013:CS470-AI:PotentialFieldsLab:Screenshot from 2013-09-28 18&%38&%53.png | Total with Goal and Tangential Modification  Macintosh HD:Users:clm:Desktop:BYU-FALL-2013:CS470-AI:PotentialFieldsLab:Screenshot from 2013-09-28 18&%46&%23.png |

* Graphs Of Potential Fields (From Red’s Perspective)

**You will need to test your PF agent as follows:**

1. **Run your pf agent against your "Really Dumb Agent". Your pf agent should win, although you will have to do some tuning to win**

I didn’t win the first time! I got stuck in a black hole of goals. I thought simply summing all of the attractive fields to each goal would pull a time into the closest goal. Upon actually thinking about this it was obvious this wouldn’t work. So, I modified my goal so that a tank will only go after one goal at a time. The selection of this goal is simply the closest goal from a list of all possible goals. This did the trick.

The second mod I had to make was the return to base goal. So after getting a flag I simply change a tanks goal to the center of its base.

1. **Run against two dumb agents, you should win**

The really dumb agents can get off some effective shots on occasion. I won! Not much that was new here.

1. **Run your pf agent against another copy of itself**

Even though there is no AI to return ones flag, red was able to return their flag several times because then ended up on the same shortest distance path between their enemy’s base.

I also saw a major bug in my code. I noticed that when a tank was forced to go strictly in the – or direction the error would explode and cause the tank to nuts as the error bounced between and –. I had to modify the code to perform a transformation between tank coordinates and 2.

1. **Find another group, run your pf against their "Really Dumb Agent", you should win again**

First of all I won! Second, one interesting observation is that the delay over the network caused my tanks to slightly overshoot their goals. The tanks had a little too much velocity and would overshoot the flag slightly every time. There seems to be a little more variance over a network versus running on localhost.

Really not much here, they run around like crazy, I capture their flag and return it.

1. **Run against two dumb agents from the other group, you should be able to win**

Won like a boss.  
In all of my trials I never had friendly fire turn on. So, during the trials my tanks obliterate each other. I need a much more complicated firing algorithm.

Again, they ran around, I captured the flag and returned it.

1. **Run your pf agent against their pf agent. Note that your grade does NOT depend upon which team wins, but it does depend upon what conclusions you can draw from the experience.**

One complicated part of this project was translating tank coordinates into a continuous space. His agents had a hard time with this calculation and would occasionally get stuck spinning in circles. Also, part of the reason that I won the game was because of the speed at which my tanks were moving. My tanks were much more effective at getting to the shortest path and then accelerating the maximum speed. I was able to capture the flag at twice his rate. In other words, speed and distance traveled were a big deal.

**PFAgent Complete Code**

|  |
| --- |
| import sys  import math  import time  from myPrint import \*  from bzrc import BZRC, Command  ###########################Potential Field Fun############################################  ####################################################################  # Distance between two points.  ####################################################################  def distance(x,y,goal):  return math.sqrt(((goal.y - y)\*(goal.y - y)) + ((goal.x - x)\*(goal.x - x)))  def distancePoints(x,y,xg,yg):  return math.sqrt(((yg - y)\*(yg - y)) + ((xg - x)\*(xg - x)))  def sign(a):  if a == 0 or a == -0:  return 0  return a / -a  ####################################################################  # Generate a Single Repulsive feild.  ####################################################################  def generateAnRepulsiveField(x,y, obsticle, makeItTangent=False, goal=None):  r = distancePoints(obsticle[0][0],  obsticle[0][1],  obsticle[2][0],  obsticle[2][1]) / 2.0  center = (obsticle[0][0] + ((obsticle[2][0] - obsticle[0][0]) / 2.0),  obsticle[0][1] + ((obsticle[2][1] - obsticle[0][1]) / 2.0))  s = 60.0  b = 1.0/s  d = distancePoints(x,y,center[0], center[1])  theta = math.atan2(center[1] - y, center[0] - x)    dx = -math.cos(theta)  dy = -math.sin(theta)    if makeItTangent:  thetaL = theta - (math.pi / 2.0)  thetaR = theta + (math.pi / 2.0)    dxL = -math.cos(thetaL)  dyL = -math.sin(thetaL)    dxR = -math.cos(thetaR)  dyR = -math.sin(thetaR)    if distancePoints(x + dxL, y + dyL, goal.x, goal.y) < distancePoints(x+dxR,y+dyR,goal.x,goal.y):  dx = dxL  dy = dyL  else:  dx = dxR  dy = dyR      temp = None  if d < r:  temp = (dx \* s, dy \* s)  elif r <= d and d <= s+r:  temp = (b \* (s + r -d) \* dx, b \* (s + r - d) \* dy)  elif d > s+r:  temp = (0,0)    return temp  ####################################################################  # Calculate repulsive fields on a given location.  ####################################################################  def generateRepulsiveField(x, y, obsticles):  total = [0,0]    for o in obsticles:  temp = generateAnRepulsiveField(x,y,o)  total[0] += temp[0]  total[1] += temp[1]    return total  ####################################################################  # Generate a single atractive vector.  ####################################################################  def genAnAttractiveField(x, y, goal):  r = 1.5  s = 30.0  al = 1.0/s    d = distance(x,y,goal)    theta = math.atan2(goal.y - y, goal.x - x)    temp = None  if d < r:  temp = (0.0,0.0)  elif r <= d and d <= s+r:  temp = (al\*(d-r)\*math.cos(theta), al\*(d-r)\*math.sin(theta))  elif d > s+r:  temp = (al\*s\*math.cos(theta), al\*s\*math.sin(theta))    return temp  ####################################################################  # Return the closest goal.  ####################################################################  def getMinGoal(x,y,goals):  amin = distance(x,y,goals[0])  minGoal = goals[0]    for g in goals:  temp = distance(x,y,g)  if temp < amin:  minGoal = g  amin = temp    return minGoal  ####################################################################  # Genertes the attractive vector given every possible goal.  ####################################################################  def generateAttractiveField(x, y, goals):  total = [0,0]    minGoal = getMinGoal(x,y,goals)    return genAnAttractiveField(x,y,minGoal)  ####################################################################  # Calculate a Tangential field  ####################################################################  def generateTangentialFields(x, y, obsticles, goal):  total = [0,0]    for o in obsticles:  temp = generateAnRepulsiveField(x, y, o, True, goal)  total[0] += temp[0]  total[1] += temp[1]    return total  ####################################################################  # Generate the potential field for a given point.  ####################################################################  def generatePotentialField(x,y,flags,obsticles):    tan = generateTangentialFields(x,y,obsticles, getMinGoal(x,y,flags))  att = generateAttractiveField(x,y,flags)  rep = generateRepulsiveField(x,y,obsticles)    return (tan[0] + att[0] + rep[0],  tan[1] + att[1] + rep[1])  ####################################################################  # Struct: basically a point (x,y)  ####################################################################  class HomeBaseCenter(object):  def \_\_init\_\_(self, x, y):  self.x = x  self.y = y  ####################################################################  ####################################################################  ## Agent  ####################################################################  ####################################################################  class Agent(object):  """Class handles all command and control logic for a teams tanks."""    ####################################################################  # Constructor  ####################################################################  def \_\_init\_\_(self, bzrc):  self.bzrc = bzrc  self.constants = self.bzrc.get\_constants()  self.obsticles = self.bzrc.get\_obstacles()  self.commands = []  self.error0 = 0    bases = self.bzrc.get\_bases()  for base in bases:  if base.color == self.constants['team']:  self.homeBase = base    self.homeBaseCenter = HomeBaseCenter(self.homeBase.corner1\_x +  ((self.homeBase.corner3\_x - self.homeBase.corner1\_x) / 2.0),  self.homeBase.corner1\_y +  ((self.homeBase.corner3\_y - self.homeBase.corner1\_y) / 2.0))    self.timeSet = [0,0,0,0,0,0,0,0,0,0] #For deltaTime  self.error0 = [0,0,0,0,0,0,0,0,0,0] #For deltaError    ####################################################################  ####################################################################  def tick(self, time\_diff):  mytanks, othertanks, flags, shots = self.bzrc.get\_lots\_o\_stuff()    self.mytanks = mytanks  self.othertanks = othertanks  self.flags = self.removeMyFlag(flags)  self.shots = shots  self.enemies = [tank for tank in othertanks  if tank.color != self.constants['team']]    #Clear Commands  self.commands = []    for tank in mytanks:  self.sendToCaptureFlag(tank, time\_diff)    results = self.bzrc.do\_commands(self.commands)    ####################################################################  # Determine if capturing a flag or returning it.  ####################################################################  def determinedGoals(self, tank):  if tank.flag == '-':  return self.flags  else:  return [self.homeBaseCenter]    ####################################################################  # Return the potential field to lead a tank home.  ####################################################################  def generateHomePotentialField(self,x,y):  return generatePotentialField(x,y,[self.homeBaseCenter],self.obsticles)    ####################################################################  # Perform calculations from a potential field and translate them  # into a speed and anglular velocity for a tank.  # PDControlor for Angular velocity.  ####################################################################  def sendToCaptureFlag(self, tank, time\_diff):  self.Kp = 0.60  self.Kd = 0.50    deltaPosition = generatePotentialField(tank.x, tank.y,  self.determinedGoals(tank),  self.obsticles)    newTheta = math.atan2(deltaPosition[1], deltaPosition[0])  newTheta = newTheta + 2 \* math.pi if newTheta < 0 else newTheta  posTankAngle = tank.angle + 2 \* math.pi if tank.angle < 0 else tank.angle    #Calculate the error  error = newTheta - posTankAngle  error = error - 2 \* math.pi if error > math.pi else error    #PDController  derivative = (error - self.error0[tank.index])/ (time\_diff - self.timeSet[tank.index])  newAngleVelocity = (self.Kp \* error) + (self.Kd \* derivative)    #Calculate Speed as a function of angular velocity  speed = math.sqrt(math.pow(deltaPosition[0], 2) + math.pow(deltaPosition[1], 2))  tempAngle = math.fabs(newAngleVelocity)  if tempAngle >= 1:  speed = 0.0  else:  speed = 1.0 - tempAngle    #Generate Command  captureFlagCommand = Command(tank.index, speed, newAngleVelocity, True)  self.commands.append(captureFlagCommand)    #Save error and time for derivative  self.error0[tank.index] = error  self.timeSet[tank.index] = time\_diff    return    ####################################################################  # Set command to move to given coordinates.  ####################################################################  def move\_to\_position(self, tank, target\_x, target\_y):  target\_angle = math.atan2(target\_y - tank.y,  target\_x - tank.x)  relative\_angle = self.normalize\_angle(target\_angle - tank.angle)  command = Command(tank.index, 1, 2 \* relative\_angle, True)  self.commands.append(command)    ####################################################################  # Make any angle be between +/- pi.  ####################################################################  def normalize\_angle(self, angle):  angle -= 2 \* math.pi \* int (angle / (2 \* math.pi))  if angle <= -math.pi:  angle += 2 \* math.pi  elif angle > math.pi:  angle -= 2 \* math.pi  return angle    ####################################################################  # Remove my flag from the list.  ####################################################################  def removeMyFlag(self, flags):  temp = None  for f in flags:  if f.color == self.constants['team']:  temp = f    flags.remove(temp)  return flags    ####################################################################  # Return all of the flags in the game save my own.  ####################################################################  def getTargetFlags(self):  return self.removeMyFlag(self.bzrc.get\_flags())    ####################################################################  # Make any angle be between +/- pi.  ####################################################################  def printPFields(self):  obsticles = self.bzrc.get\_obstacles()  flags = self.getTargetFlags()    #printer = PFPrinter('aFields.gpi')  #printer.printObsticles(obsticles)  #printer.printPotentialFields(lambda x,y: generateAttractiveField(x, y,flags))    #printer = PFPrinter('rFields.gpi')  #printer.printObsticles(obsticles)  #printer.printPotentialFields(lambda x,y: generateRepulsiveField(x, y, obsticles))    #printer = PFPrinter('tFields.gpi')  #printer.printObsticles(obsticles)  #printer.printPotentialFields(lambda x,y: generateTangentialFields(x, y, obsticles))    printer = PFPrinter('homeFields.gpi')  printer.printObsticles(obsticles)  printer.printPotentialFields(lambda x,y: self.generateHomePotentialField(x, y))    printer = PFPrinter('pFields.gpi')  printer.printObsticles(obsticles)  printer.printPotentialFields(lambda x,y: generatePotentialField(x, y, flags, obsticles))  def main():  # Process CLI arguments.  try:  execname, host, port = sys.argv  except ValueError:  execname = sys.argv[0]  print >>sys.stderr, '%s: incorrect number of arguments' % execname  print >>sys.stderr, 'usage: %s hostname port' % sys.argv[0]  sys.exit(-1)    # Connect.  #bzrc = BZRC(host, int(port), debug=True)  bzrc = BZRC(host, int(port))    agent = Agent(bzrc)    prev\_time = time.time()    # Run the agent  try:  while True:  time\_diff = time.time()  agent.tick(time\_diff)  except KeyboardInterrupt:  print "Exiting due to keyboard interrupt."  bzrc.close()  if \_\_name\_\_ == '\_\_main\_\_':  if len(sys.argv) == 4:  execname, host, port, printMe = sys.argv    if printMe == "-p":  bzrc = BZRC(host, int(port))  agent = Agent(bzrc)  agent.printPFields()  bzrc.close()    else:  main() |

**Really Dumb Agent Complete Code**

|  |
| --- |
| import sys |
| import math |
| import time |
| import random |
|  |
| from bzrc import BZRC, Command |
|  |
| class Agent(object): |
| """Class handles all command and control logic for a teams tanks.""" |
|  |
| def \_\_init\_\_(self, bzrc): |
| self.bzrc = bzrc |
| self.constants = self.bzrc.get\_constants() |
| self.commands = [] |
|  |
| self.counter = 0 |
| self.forwardCount = 8 |
| self.shootCount = 2 |
|  |
| def tick(self, time\_diff): |
| """Some time has passed; decide what to do next.""" |
| mytanks, othertanks, flags, shots = self.bzrc.get\_lots\_o\_stuff() |
| self.mytanks = mytanks |
| self.othertanks = othertanks |
| self.flags = flags |
| self.shots = shots |
| self.enemies = [tank for tank in othertanks if tank.color != |
| self.constants['team']] |
|  |
| self.commands = [] |
|  |
| self.counter += 1 |
|  |
| for tank in self.mytanks: |
| self.moveForwardOrTurn(tank) |
| self.randomShoot(tank) |
|  |
| results = self.bzrc.do\_commands(self.commands) |
|  |
| def moveForwardOrTurn(self, tank): |
|  |
| if self.counter < 80: |
| #Go Forward |
| command = Command(tank.index, 1.0, 0.0, False) |
| self.commands.append(command) |
| elif self.counter > 70 and self.counter < 160: |
| #Stop and Turn |
| command = Command(tank.index, 0.5, 1.0, False) |
| self.commands.append(command) |
| else: |
| #Reset |
| self.counter = 0 |
|  |
| return |
|  |
| def randomShoot(self, tank): |
| test = random.random() |
| if test < .5: |
| command = Command(tank.index, 0, 0, True) |
| self.commands.append(command) |
| return |
|  |
|  |
| def main(): |
| # Process CLI arguments. |
| try: |
| execname, host, port = sys.argv |
| except ValueError: |
| execname = sys.argv[0] |
| print >>sys.stderr, '%s: incorrect number of arguments' % execname |
| print >>sys.stderr, 'usage: %s hostname port' % sys.argv[0] |
| sys.exit(-1) |
|  |
| # Connect. |
| #bzrc = BZRC(host, int(port), debug=True) |
| bzrc = BZRC(host, int(port)) |
|  |
| agent = Agent(bzrc) |
|  |
| prev\_time = time.time() |
|  |
| # Run the agent |
| try: |
| while True: |
| time\_diff = time.time() - prev\_time |
| agent.tick(time\_diff) |
| except KeyboardInterrupt: |
| print "Exiting due to keyboard interrupt." |
| bzrc.close() |
|  |
|  |
| if \_\_name\_\_ == '\_\_main\_\_': |
| main() |