Research Statement

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Decision making or planning optimize the robots' behaviors to transit the real-world towards desired states. Planning for real-world tasks is extremely challenging. The world can be highly complex and dynamic, while robots only have limited sensing capabilities. Planning algorithms thus need to handle a plethora of uncertainties [8]: imperfect robot control, noisy sensors, and fast-changing environments.

Planning becomes particularly challenging when involving many human participants interacting intensively with each other and the robot. A representative example is driving among a crowded traffic, where a robot vehicle interacts with many partially observable traffic participants. A large crowd induces a high-dimensional state space, highly-complex dynamics and uncertain human behaviours, which raises enormous difficulties in perception, prediction, and planning. To act safely and efficiently in such environments, sophisticated long-term planning is required, which additionally requires accurate models and efficient solvers.

I dedicate my research to large-scale decision making in complex and highly-interactive environments, especially those involving uncertainties and long-term planning. I aim to tackle crowded, chaotic environments and enable robots to accomplish complex tasks safely and efficiently. I have developed models and algorithms been validated on a variety of tasks: classical planning benchmarks, real-world industrial environments, and autonomous driving in crowded traffic. My work brings practical solutions to large-scale, long-term planning by focusing on three aspects: human behaviour modelling, real-time planning, and integration with learning. Specifically:

1) traffic agent motion models for accurate long-term predictions and realistic simulations;
2) massively-parallel planners for real-time planning in large-scale environments;
3) integration of planning and learning to to solve complex long-term planning tasks.

The following sections present the three aspects in detail.

Traffic motion models and crowd simulation

A "good" model not only needs to accurately model the complexity of real-world dynamics and human behaviours, but also needs to capture the intrinsic uncertainties in principled ways. We have formalize the interaction among human traffic participants as constrained optimization in the velocity space. Constraints of the problem encodes kinematic and collision avoidance constraints of traffic participants; Objective of the problem is to navigate efficiently towards the intended goals. Using this formulation, we proposed two traffic motion models: PORCA [11] for pedestrians and GAMMA [10] for mixed traffic. Both models can be solved using quadratic programming in linear time. The efficiency of these models enables integration to real-time crowd-driving algorithms. The power of using these models in planning has been demonstrated in both driving among pedestrians and urban driving [12].

Fig. 1. Driving among an unregulated traffic crowd. Left: real-world scene (Africa); Right: simulated scene in the SUMMIT simulator.

Importantly, our motion models are conditioned on human factors such as intention, attention, willing to take responsibility. These factors are not observable, but can be effectively inferred using Bayesian filtering from the interaction history of traffic participants. This filtering process helps to produce accurate and highly-variable motion predictions.

Building upon these motion models, we have developed an driving simulator, SUMMIT [5], for simulating unregulated urban crowds. The simulator parses online, real-world maps to construct realistic driving scenes and executes the motion models to simulate highly-interactive heterogeneous traffic. The purpose of the simulator is to provide unlimited amount of highly-interactive driving scenes to enable developing, training, and evaluating driving algorithms that tackle important problems such as perception, motion prediction, control, decision making, and end-to-end learning.

The model models has been published in RAL[11] and available on Arxiv [10]. A collaborative work [12] presented in IROS 2019 demonstrates planning using the motion models in an real-world urban environment. The SUMMIT simulator is to be presented in ICRA 2020 [5] with open-source code to be released soon.

Large-scale planning under uncertainty

Real-world robots have to contend with a complex and uncertain environment. It often requires sophisticated long-term planning to achieve human-level performance. Unfortunately, long-term planning brings combinatorial complexities, also known as the "curse of dimensionality" and the "the curse of history" [7]: the complexity of optimal planning grows exponentially with the problem scale and the planning horizon. Practical planning algorithms are in urgent demand.

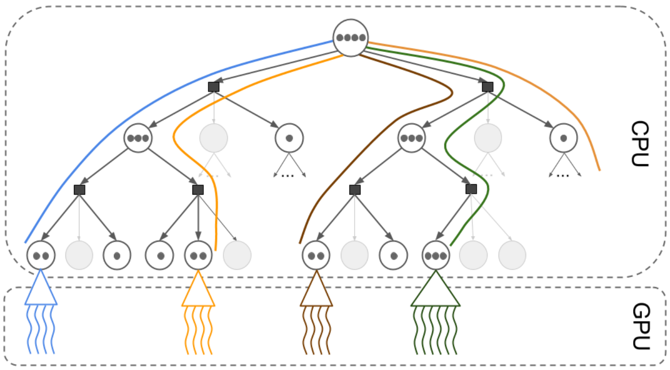

Fig. 2. An illustration of the HyP-DESPOT algorithm, a massively parallelized belief tree search algorithm for large-scale planning under uncertainty.

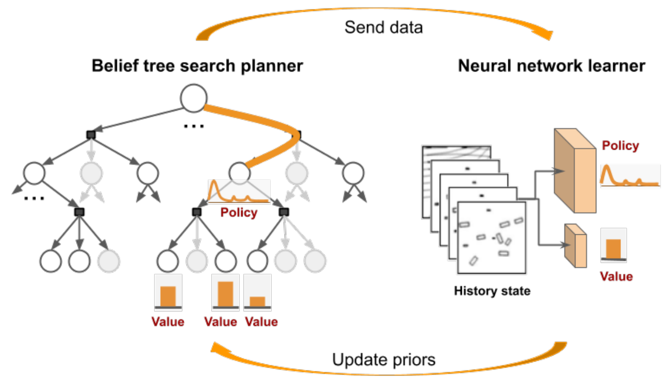

Fig. 3. An illustration of LeTS-Drive: constrain search to short-term futures, and use learning to account for long-term futures.

My idea to scale-up planning is massive parallelization. My early attempts focused on parallelizing motion planning in industrial environments. I developed real-time motion planners for crane-lifting in highly-complex industrial sites [2, 3]. The algorithms uses parallel Genetic Algorithms to plan globally-optimal paths and uses parallel pixel-space checking to detect collisions. Both the planner and the collision checker are integrated in a single hierarchical GPU parallelization scheme to achieve real-time performance.

This line of work has been published in IEEE Transactions on Industrial Informatics (TII) [3] and Automation in Construction (AIC) [2].

A greater challenge in robotics is to handle stochastic environments and partial observability in large-scale problems. Such problems are often solved in the belief space [7]: the space of probability distributions over possible system states. State-of-the-art algorithms perform online belief tree search [13, 14]: at each time step, look-ahead from the current belief to search an optimal action. The system then execute the action, receive observations from sensors, update the belief, and enter the next planning cycle. Belief tree search offers a principled way to perform online planning under uncertainty. However, it still suffers from the combinatorial complexity and requires additional techniques to scale-up.

I have developed a massively-parallelized belief tree search algorithm, HyP-DESPOT [4], to scale up to large-scale problems. The core idea is to integrate CPU and GPU parallelization: use CPU cores to parallelize irregular tasks, i.e., the tree search, and use GPU cores to parallelize regular tasks, i.e. roll-outs at leaf nodes. By doing so, HyP-DESPOT achieves hundreds of times of speed-up in various large-scale planning benchmarks, and enables a robot vehicle to drive among crowds of pedestrians safely and efficiently.

This line of research has been published in Robotics: Science Systems (RSS 2018) [4] and is currently under review by the International Journal of Robotics Research (IJRR). I have open-sourced the parallel planner with a general API for users to easily plugin their problem models and boost real-time planning for their own tasks.

Integrating Planning and Learning

Long-term planning has several inherent problems: combinatorial complexity w.r.t. the planning horizon, accumulative model errors, and exponentially decreased coverage of Monte Carlo simulations. I seek to integrate planning with learning to benefit from both the robustness of explicit reasoning and the capability to learn from data. I propose a principle for integrating planning and learning: “think locally and learn globally”, specifically, constrain search to short-term futures, and use learning to account for long-term futures.

Following this principle, I have developed a crowd-driving algorithm, LeTS-Drive [6], that integrates offline imitation learning [1] with online belief tree search. LeTS-Drive learns two global priors from offline data: a policy function and a value function, both represented as neural networks [9]. During online planning, the prior policy is used to guide the belief tree search, and the prior value function is applied to initialize value estimations at leaf nodes. In effect, the learned priors encode a global policy and the belief search improves over this prior policy through additional, explicit reasoning for local futures. Applying this integration scheme, LeTS-Drive achieved superior driving performance among highly interactive crowds, and outperforms either planning or learning alone.

This line of research has been published in RSS 2019 [6]. I am continuing to explore the research question that how planning can be performed locally, how learning can be performed globally, and what the best ways are to combine them in different problem setups.

Summary

I seek principled solutions to attack complex real-world problems. I propose mathematically-sound formulations of real-world problems and develop principled algorithms to solve them efficiently. I believe that explicit, sophisticated reasoning is the key towards super-human intelligence. I have grounded this belief and dedicated my efforts to human behaviour modeling, parallel real-time planning, and integrating planning with learning.

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