Artificial Intelligence for Games
Developing an AI agent for the game of Tanks based on the subsumptive architecture

Connor Aspinall (13021267) George Bell (13025221)
Denis Torgunov (13011546)

Abstract

This report details the design and implementation of an AI player for a game of Tanks, based on a subsumptive architecutre. We highlight the improvements to our pathfinding module based on what we have learned during our work on the previous coursework, as well as detail our own implementation of subsumptive dispatch. We mention some of the issues we had during development and provide suggestions for future work and improvement.

Contents

1 Introduction

This report details the implementation of a subsumption-based AI, as developed by the group "Team $-i^2$". The implemnetation focuses on an adaptive approcah and uses A* for effiecent pathfinding and navigation. It is meant to be extendible and the implementation produced, while succesful[1] during testing, was envisoned more as a proof of concept, with suggestions on better levereging the approach proposed given in section 4.

Due to the fact that most of the codebase had to be implemented from scratch, as well as time constraints, the resulting AI might not be sufficiently optimised, and therefore unable to utilise CPU time provided in the most efficient manner. Suggestions for further optimisation are also given in section 4.

2 AI Design and Implementation

The AI produced by our group for this coursework focuses on utilising a subsumption architecture, inspired by the work done by one of the group members in the context of intelligent robotics. The subsumptive architecture, as proposed by Brooks, aims to form close connections between sensory inputs and behaviours of an intelligent agent [1]. In the context of an intelligent Tanks player, we can take information gleamed from the state of the map as simulating sensory inputs, and define a series of behaviours (such as running away, exploring, or seeking an enemy) to take in specific situations. This approach lends itself well to group work, as individual components and behaviours can be developed separately, and then combined in arbitrairly complex ways using the subsumption architecture.

The binding of game situations (sensory inputs) to behaviours can be changed dynamically, or assigned at the start. For the purposes of this coursework, we define 2 major "behavious profiles" (as discussed in section 2.2), a "Hunter" and an "Explorer". For the discussion of potential for dynamic and adaptive behaviour see section 4.

2.1 Subsumptive Control

In order to make it possible to implement the subsumptive control system, we have created a class, `SubsumptionDispatch`, which calls the corresponding action when the right "stimulus" occurs. For the full source code listing please see section **??**. In this section we will only highlight the central parts of the implementation.

Firstly, we make use of C# delegates to allow us to use higher-order methods, passing methods around as values and evoking them when needed. Specifically, we define the following two delegates:

```
public delegate bool Situation();
public delegate ICommand Action();
```

A `Situation` is a predicate that represents a situation in the game, corresponding to sensory input in a traditional subsumption architecture. An `Action` represents a method that returns the next command to execute, corresponding to operating an acutator. It is assumed to take no arguments, relying purely on the internal state of the main class for any information about map composition, current player position, etc.

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[1] was it?

Having defined those delegates, we can implement a dispatch table as a linked list of tuples:

```
private List<Tuple<Situation, Action>> dispatchTable;
```

We assume that the first element in the list has the highest priority. If its `Situation` arises, we execute the corresponding `Action`. Otherwise, we continue down the list. We assume that at least one of the `Situation`s will occur. In order to ensure that, the final element of the list should be a "default" action: simulated using a predicate that is always true.

With those definitons, we can now create the main program loop: the `act()` method:

```
public ICommand act()
{
  foreach (Tuple<Situation, Action> behaviour in dispatchTable)
  {
    if (behaviour.Item1())
    {
      return behaviour.Item2();
    }
  }
  return null;
}
```

As soon as the `Action` with a matching `Situation` is found, we simply execute that action, returning the corresponding command to be executed on this turn.

2.2 Behaviour Profiles

We consider two possible behaviour profiles for this AI: the Hunter and the Explorer. The goal of the game is to maximise the score, and the behaviour process aims to do so in the most efficient way. If exploration is more valuable, point-wise, than killing opponents, we can utilise the Explorer profile, which focuses primarily on discovering the map and avoiding confrontation. On the other hand, if the amount of points received for killing an enemy is higher than the amount of points gained (on average) through exploration, we utilise the Hunter profile, which will actively seek to destroy enemy tanks.

Figure 1 outlines the Explorer behaviour profile, and figure 2 outlines Hunter. The Explorer aims to explore as much of the map as possible, while allowing the enemies to fight amongst themselves, only going on the offensive when there is a single enemy left. On the other hand, the Hunter actively seeks to gain points by destroying enemy tanks, and only then explores the remaining parts of the map.

The choise of behaviour profile largly depends on which appraoch would be more profitable, in terms of points, on a given map. However, since we did not have sufficient data regarding how either profile performs against other AI opponents (see section 3 for details), we instead choose to randomise the choise, making it possible for either approach to be chosen when the AI is first loaded in. But, in order to maximise our chanses of winning, we bias the randomisation based on score gains for a given terrian.

In particular, as mentioned above, Hunter aims to gain points for killing enemy tanks before other players can do so. But we can only destroy 3 tanks in total, and the gain in points might not be worth the risk. On the other hand, Explorer attempts to avoid

confrontation, which might allow the enemy to cut us off from certain portions of the map, diminishing our score.

In the end, we chose to use the following metric: if the average gain for exploring 3/4 of the map is higher than the points gained for killing all 3 tanks, we bias the random profile chooser towards Explorer. Otherwise, the bias is towards Hunter. The "biased" profile has a 60% chance of being picked.

Since the default action implies that there are no enemies left and all of the map has been explored, we simply stay still, as there are no further points to be gained.

2.3   Mapping and Pathfinding

In order to make it easier to navigate and seek out enemies, we keep track not only of the visible area, but also of the overall map explored so far. To that end, we have defined a `Cell` enum. We keep and update an array of `Cell`s, filling it with the "visible" information on each turn. [2]

We also keep track of the last place we saw enemy tanks, to make it easier to avoid or chase them later. This means that we also have to "prune" the map every so often, making sure there is at most one instance of each enemy (the one we saw most recently). For more details, please see section **??**.

The pathfinding algorithm we use is a refined and improved version of the A* implementation used in our previous coursework submission [2]. We have cleaned up the `GridNode` class, making it more streamlined, smaller and easier to use by removing redundant accessor functions. Since the class is only ever used within the project and no pre-processing of parameters is necessary, and no guarded conditions exist that could be enforced by, we simply made the relevant fields public. The only exception is `GridNode.fCost`, which has been replaced with a getter that simply returns the relevant value, computed based on the other parameters. This reduces the risk of `GridNode.fCost` not being updated properly by mistake.

In addition, we also have completely restructured the main pathfinding logic, in order to remove errors previously present. We have levereged what we have learned while implementing the first iteration [2] and improved on the main shortcomings.

The most significant changes are as follows:

- Fixed an issue which caused the `GridNode.fCost` to be set inconsistantly while constructing the list of neighbours.

- Fixed an issue where the path returned is not gaurenteed to be the shortest path as some `GridNode`s where skipped unnecessarily.

- Optimised the implementation by sorting the list to act as a priority queue, potentially reducing CPU time (depending on the native .NET sort implementation).

- To improve code readability, we use a stack when listing neighbours. We loop through the stack's contents instead of considering each neighbour explicitly when testing whether a coordinate is within the bounds of the board array. Previously, a nested loop was
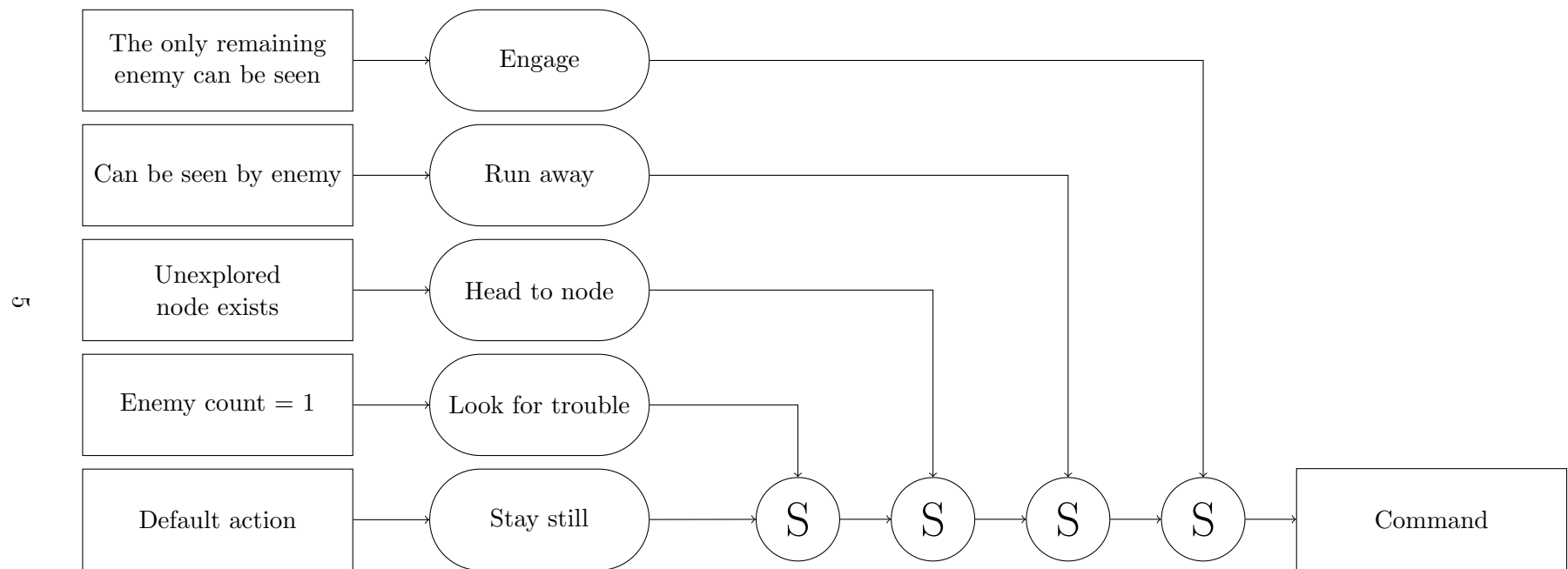
---

[2]What the word?

Figure 1: The Explorer profile

```
┌──────────────────┐      ╭──────────────────╮
│  Enemy sighted   │ ───→ │      Engage      │ ──────────────────────────┐
└──────────────────┘      ╰──────────────────╯                           │
                                                                         │
┌──────────────────┐      ╭──────────────────╮                          │
│  Enemies exist   │ ───→ │   Seek enemy     │ ──────────────┐          │
└──────────────────┘      ╰──────────────────╯               │          │
                                                              │          │
┌──────────────────┐      ╭──────────────────╮               │          │
│    Unexplored    │ ───→ │   Head to node   │ ──┐           │          │
│   nodes exist    │      ╰──────────────────╯   │           │          │
└──────────────────┘                             ↓           ↓          ↓
┌──────────────────┐      ╭──────────────────╮  ( S ) ──→  ( S ) ──→  ( S ) ──→  ┌──────────────┐
│  Default action  │ ───→ │    Stay still    │ ─→                                 │   Command    │
└──────────────────┘      ╰──────────────────╯                                    └──────────────┘
```
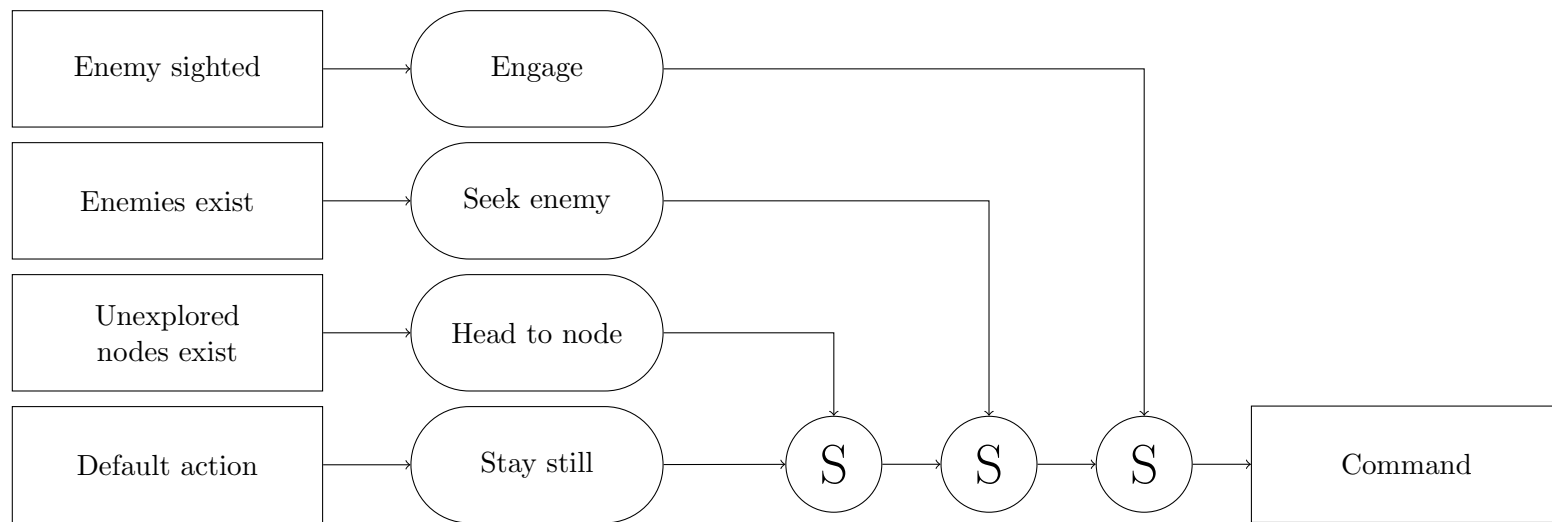
Figure 2: The Hunter profile

used, but the corrent approach, in addition to making the code easier to understand, also reduces complexity.

For the full listing of the pathfinding code please see section **??**.

Furthermore, as several actions in our behaviour profiles involve navigating to unexplored parts of the map, we needed a reliable way to determine which unexplored cells we could navigate to. In order to achive that, we have implemented a function `LocationLocator.UnexploredNode()`, which returns a node at the edge of the currently explored region and not behind a potential wall, if such a node exists. The full code listing is available in section **??**, and is based on [3].

2.4   Actions

The actions that are carried out by the AI are dictated by the Subsumption Dispatch Table, which calls the relevant method in the class `LocationLocator` that, in turn, attempts to find the best location to travel to in the given situation. This is achieved by having several methods, each relevant to one of the potental calls from the Subsumption Dispatch Table, with one being called each turn.

2.4.1   Retreating

One of these key actions that can be carried out under the Explorer profile (as can be seen in Figure 1) is the run away action. This allows the AI to retreat when threated by an opponent, with the corresponding action being found in the method `LocationLocator.Retreat()`. The full source code is listed in section **??**. This method begins by generating a `List` of `GridNode`s found around the player that contain an obstacle that can be hidden behind. This list is initially generated from a 3-by-3 area which is centred on the player, however this will be expanded if no suitable hiding locations are found. Due to the increasing complexity of this algorithm upon expansion [4], it is capped at an area of 5-by-5, or an additional `GridNode` in each direction. If, after analysing an area of that size we find no suitable cover, it will default to dodging in a random direction until it moves closer to something it can take cover behind.

Upon finding a valid piece of cover, the AI will check behind it to see if it is a valid location. This is done by comparing the value of the `Cell` to that of `Cell.Empty`. Initally, this is done by looking at any obstacles in the four cardinal directions within GridWorld (Up, Down, Left and Right) and check the side opposite the player. If the these locations are not valid, or if no obstacles exist in these positions, the AI checks the corner `Cell`s. These can potentionally have two seperate locations where the tank can hide, so both the furtherest X and Y locations (relative to the player) must be checked. Again, if there is a valid location to move to and hide at, it will do so, but if there is not then the AI defaults back to the `LocationLocator.RandomDodge()` method.

`LocationLocator.RandomDodge()`, which is used when no hidding places are found close to the player, works to determine where the player should move. The randomness is included so that, if there are multiple moves possible at a given time, it will choose one that cannot be predicted. This behaviour is often seen in video games [5], as it can lead to unexpected events occuring for the player, although it is also helpful in this scenario as it enables the AI to be slightly unpredictable, potentally dealing with opponents that implemtent machine learning.

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2.4.2 Attacking

The key action from the Hunter profile (Figure 2) is to find and kill a visible opponent. This action is carried out in the `LocationLocator.Attack()` method, which accepts the following arguements:

- The `GridSquare` that contains the opponent to attack.

- A `PlayerWorldState.Facing` that represents the direction the AI is facing.

- The `Command` to be executed if the opponent cannot be attacked directly.

To begin with, the method calculates if it is possible to kill the opponent this turn, proceeding to do so if it is possible. This is achieved by checking if the AI and the opponent share either an X or a Y coordinate. If they do, then the AI calculates whether the tank is currently facing the opponent, before either attacking, or rotating and then attacking the given opponent. If this is not the case, then the `Command` is returned, which is part of a path for the AI to follow towards the opponent. As the tank can only move in four directions, and cannot shoot diagonally, this ensures that the tank will reach a point from which it can attack the given enemy.

3 Testing and Tuning

In order to test pathfinding and exploration without the oppontent AI destroying us, we have implemented a simple "Useless" AI, following the logic described in the lecture notes, that simply stays stationary and avoids attacking. This allowed us to safely navigate around the map and discover the bugs in the exploration part of the code.

In addition, problems arouse due to unexpected errors coming from Visual Studio. Firstly, we got errors trying to load the (standard) `Tuple` class, so we have implemented our own, adhereing to the same naming conventions for elements [6], to make it interoperate with the code already written. In addition, similar errors appeared as the development progressed. Eventually, we have decided to try changing the .NET framework version used by the IDE to 3.5, and while that seemed to resolve the issue, it gave us cryptic warnings that we did not have time to investigate in detail and that might account for some of the bugs.

Due to problems accessing the GridWorld server, all of our testing had to be carried out locally, utilising either the "Useless" AI or the stock AI provided. Originally, we were going to tune the performance of the agent by experimenting with different priorities and actions in the behaviour profiles, but as real world performance data was unavailable, it could not be done reliably.

However, a small element of "learning" has been noticed during testing. Specifically, if the AI is not reloaded, but the game is simply "rewound" to the first turn, we still retain the map layout explored during the previous game.

A few errors have revealed in testing, and subsequently fixed, but overall more refinement is needed before the AI is able to win consistently. In particular, perhaps instead of choosing random cells when exploring or seeking enemies, we need to apply some sort of heuristic that will lead to better overall score.

The only issue we have found is, if multiple AIs are loaded in Explorer mode, they come to a stailmate, as they explore all they can, and then stay still until there is only a single enemy left, which never happens, leading to a tie.

4 Recommendations for Future Work

As mentioned earlier in section 2, it is possible to make this AI better by, instead of providing predefined behaviour profiles, introducing a machine learning aspect by allowing the AI to learn, throughout the game, to associate specific `Situation`s with the best `Action`s, as well as adjusting the priority of each binding accordingly. Genetic programming might be a good fit for such a task. However, because it is impossible to save the information on the GridWorld servers themsevles between games, it means that the AI has to learn locally, which severely limits the applicability of this approach within the given setup.

The actions and predicates themselves could be further refined and optimised. As detailed in section 2.4, the complexity of some actions may be increased, allowing the AI to make more informed descions. With additonal refinement and testing, we could find the right balance between runtime and complexity. For attacking the AI carries out, the main addition to make to the predicates would be to calcutate whether the player can attack the opponent before they themselves can be attacked, enabling a form of 'fight or flight' mechanism to be implemented.

Our approach to mapping and extracting infromation from the local map kept is, most likely, the least optimised part of the implementation. In particular, we have to loop through the whole array multiple times on each game loop iteration. Combining the tests performed into a single loop and making predicates simple accessors to the boolean fields holding the information gathered this way should make the code a lot less redundant.

Finally, the pathfinding algorithm, as presented in the code, computes the path anew on each loop iteration. If the target cell has not changed, and there is no change in `Situation`, it should be possible to cache the path initially computed, and simply continue moving as needed, greatly reducing the work done on each game loop iteration.

4.1 GridWorld Recommendations

As mentioned above, the main element that we found missing in both this and the previous coursework submission for this module is the ability to retain information between runs on the GridWorld server. If each user was allocated a small amount of storage on the server, or a way to redirect some form of data to a text or binary file that could then be retrieved, it would be possible to view the server as a dynamic learning environment, broadening the applicability of machine learning approaches.

More clarity in representing the game situation and knowledge would make debugging easier. For example, some form of visulisation of a tank firing, as well as a way to simulate the agent's field of view within GridWorld.

5 Conclusions

While developing this AI, we have levereged the skills and knowledge gained both as part of this module, as well as other related subjects. It has provided us with an interesting challenge, and the final intelligent agent produced has a lot of potential. While the submitted version might not be sufficiently tested and optimised, we believe that it could form a strong foundation for an adaptive, intelligent player with emergent intelligent behaviour.

References

[1] R. A. Brooks, "How to build complete creatures rather than isolated cognitive simulators."

[2] C. Aspinall, G. Bell, M. Coyne, C. Cummings, C. Eidson, and D. Torgunov, "Artificial intelligence for games. Developing and AI agent for the game of Snails," March 2016, coursework submission for AI for Games (CM-0328D).

[3] D. Torgunov, "Intelligent robotics. Maze exploration," April 2016, coursework submission for Intelligent Robotics (CY-0330D).

[4] A. Sherrod, *Data structures and algorithms for game developers.* Cengage Learning, 2007.

[5] M. Hendrikx, S. Meijer, J. Van Der Velden, and A. Iosup, "Procedural content generation for games: A survey," *ACM Transactions on Multimedia Computing, Communications, and Applications (TOMM)*, vol. 9, no. 1, p. 1, 2013.

[6] Tuple class. Microsoft. Accessed: 04 May 2016. [Online]. Available: https://msdn.microsoft.com/en-us/library/system.tuple%28v=vs.110%29.aspx

A   Evidence of Group Work

Throughout this project's development, Github has been used in order to synchronise our work and communicate issues. Below, we list the final log of git contributions, showing that all the group members have participated. Note that, on average, people with less commits had more code added per commit. The majority of the work on the report has been done as a group.

Merge commits have been omitted from the log for brevity.

B   Source code

Please note that a curved red arrow indicates a linebreak not present in the original code, inserted for readibility.

Tuple.cs

```
using System;
using System.Collections.Generic;
using System.Collections;
using System.Linq;
using System.Text;

namespace GridWorld
{
    class Tuple<T1, T2> //: IEquatable<Tuple<T1, T2>>
    {
        public T1 Item1;
        public T2 Item2;

        public Tuple(T1 i1, T2 i2) {
            this.Item1 = i1;
            this.Item2 = i2;
        }

        public override bool Equals(Object obj) {
            if (obj == null)
            {
                return false;
            }

            Tuple<T1, T2> t2 = obj as Tuple<T1, T2>;
            if ((System.Object)t2 == null)
            {
                return false;
            }

            return (this.Item1.Equals(t2.Item1) && this.Item2.Equals(t2.Item2));
        }
```

```
        public bool Equals(Tuple<T1, T2> t2)
        {
            return (this.Item1.Equals(t2.Item1) && this.Item2.Equals(t2.Item2));
        }
    }
}
```

GridNode.cs

```
namespace GridWorld
{
    /// <summary>
    /// Stores data about each Node in the game when they are being searched.
    /// </summary>
    class GridNode
    {
        public int x;
        public int y;
        public Cell cell;
        public int hCost;
        public int gCost;
        public bool walkable;
        public GridNode parent;

        public GridNode(int x, int y, Cell cell){

            this.x = x;
            this.y = y;
            this.cell = cell;

            if (cell == Cell.Empty || cell == Cell.Hero)
            {
                walkable = true;
            }
            else
            {
                walkable = false;
            }

        }

        /// <summary>
        /// Returns the F-cost of this GridNode.
        /// </summary>
        /// <returns>The F-cost of this GridNode.</returns>
        public int fCost
        {
            get
            {
                return hCost + gCost;
            }
        }
```

```csharp
        public Tuple<int, int> ToTuple()
        {

            return new Tuple<int, int>(x, y);
        }



    }
}
```

MightPathFinder.cs

```csharp
using System;
using System.Collections.Generic;
using System.Linq;
using System.Text;

namespace GridWorld
{
    class MightyPathFinder
    {
        GridNode[,] InternalNodeMap;
        Cell[,] InternalCellMap;
        GridNode Hero;


        /// <summary>
        /// Construct class and initialise internal map representatives.
        /// </summary>
        /// <param name="ICM">Local Cell Map.</param>
        public MightyPathFinder(Cell[,] ICM)
        {
            this.InternalCellMap = ICM;
            ConvertToGridNodeArray(InternalCellMap);

        }



        /// <summary>
        /// Convert from Cell[,] to GridNode[,] and intialises internal node map.
        /// </summary>
        /// <param name="ICM">Local Cell Map.</param>
        public void ConvertToGridNodeArray(Cell[,] ICM)
        {
            InternalNodeMap = new GridNode[InternalCellMap.GetLength(0),
                ↪ InternalCellMap.GetLength(1)];

            for (int x = 0; x < InternalCellMap.GetLength(0); x++)
            {
                for (int y = 0; y < InternalCellMap.GetLength(1); y++)
                {
```

```csharp
                InternalNodeMap[x, y] = new GridNode(x, y, InternalCellMap[x, y
                     ↪ ]);

                if (InternalCellMap[x, y] == Cell.Hero)
                {
                    Hero = InternalNodeMap[x, y];
                }
            }
        }
    }

    /// <summary>
    /// Return the horizontal and vertical neighbouring nodes of a given node.
    /// </summary>
    /// <param name="node"> The current node.</param>
    /// <param name="target">The target node.</param>
    /// <returns>Return a list of all found neigbours(if any).</returns>

    private List<GridNode> GetNeighbours(GridNode node, GridNode target)
    {

        List<GridNode> neighbours = new List<GridNode>();

        Stack<Tuple<int, int>> potentialNeighbours
                = new Stack<Tuple<int, int>>();

        int x = node.x;
        int y = node.y;

        potentialNeighbours.Push(new Tuple<int, int>(x - 1, y));
        potentialNeighbours.Push(new Tuple<int, int>(x + 1, y));
        potentialNeighbours.Push(new Tuple<int, int>(x, y - 1));
        potentialNeighbours.Push(new Tuple<int, int>(x, y + 1));

        foreach (Tuple<int, int> coor in potentialNeighbours)
        {
            if (IsValidCoordinate(coor))
            {
                GridNode n = InternalNodeMap[coor.Item1, coor.Item2];
                if (n.walkable || n.Equals(target))
                {
                    neighbours.Add(n);
                }
            }
        }
        return neighbours;
    }
    /// <summary>
    /// Check if an unexplored node is traversable.
    /// </summary>
    /// <param name="node"> Node to be checked.</param>
```

```csharp
/// <returns>'True' if Traversable, 'False' otherwise.</returns>

private bool reachableUnexplored(GridNode node)
{
    if (node.cell == Cell.Unexplored)
    {
        Stack<Tuple<int, int>> potentialNeighbours
            = new Stack<Tuple<int, int>>();

        int x = node.x;
        int y = node.y;

        potentialNeighbours.Push(new Tuple<int, int>(x - 1, y));
        potentialNeighbours.Push(new Tuple<int, int>(x + 1, y));
        potentialNeighbours.Push(new Tuple<int, int>(x, y - 1));
        potentialNeighbours.Push(new Tuple<int, int>(x, y + 1));

        foreach (Tuple<int, int> coor in potentialNeighbours)
        {
            if (IsValidCoordinate(coor))
            {
                GridNode n = InternalNodeMap[coor.Item1, coor.Item2];
                if (n.walkable)
                {
                    return true;
                }
            }
        }
        return false;
    }
    else
    {
        return false;
    }
}

/// <summary>
/// Check if vector position is contained on the map.
/// </summary>
/// <param name="coor">Position.</param>
/// <returns></returns>

private bool IsValidCoordinate(Tuple<int, int> coor)
{
    if (coor.Item1 < 0 || coor.Item2 < 0)
    {
        return false;
    }

    if (coor.Item1 > InternalNodeMap.GetLength(0) - 1
      || coor.Item2 > InternalNodeMap.GetLength(1) - 1)
```

```
        {
            return false;
        }

        return true;
    }


    /// <summary>
    /// Return Matthatten heuristic value of cost for moving from one space to
    ///     ↪ an adjacent space.
    /// </summary>
    /// <param name="node">The Current Node</param>
    /// <param name="goal">The Target Node</param>
    /// <returns>Computed cost</returns>
    private int heuristic(GridNode node, GridNode goal)
    {
        int dx = Math.Abs(node.x - goal.x);
        int dy = Math.Abs(node.y - goal.y);

        return dx + dy;
    }
    /// <summary>
    /// Gets the shortest path between two given node positions.
    /// </summary>
    /// <param name="TupleNode">Target node position</param>
    /// <param name="heroPos"> Starting node position</param>
    /// <returns> List of path nodes</returns>

    public List<GridNode> GetPathToTarget(Tuple<int, int> TupleNode, GridSquare
        ↪   heroPos){

        ConvertToGridNodeArray(InternalCellMap);

        List<GridNode> open = new List<GridNode>();
        List<GridNode> closed = new List<GridNode>();

        GridNode Target = InternalNodeMap[TupleNode.Item1, TupleNode.Item2];
        GridNode heroNode = new GridNode(heroPos.X, heroPos.Y, Cell.Hero);

        open.Add(heroNode);

        while (open.Count > 0)
        {

            open = open.OrderBy(n => n.fCost).ToList(); // treat as priority
                ↪ queue
            GridNode current = open[0];
            open.Remove(current);
            closed.Add(current);

            if (current == Target)
```

```csharp
            {
                List<GridNode> path = new List<GridNode>();

                while (current != null)
                {
                    path.Add(current);
                    current = current.parent;
                }

                // reverse the path
                path.Reverse();

                return path;
            }

             List<GridNode> neighbours = GetNeighbours(current, Target);
                foreach (var n in neighbours)
                {
                    int cost = current.gCost + 1; // assume movement cost is
                        ↪ always 1 (even terrain)

                    // .Contains() should be fine, as we're getting all nodes
                        ↪ from the array above,
                    // so the node at the same position should have the same
                        ↪ address. If this causes
                    // issues, override .Equals()
                    if (open.Contains(n) && cost < n.gCost)
                    {
                        open.Remove(n);
                    }

                    if (!open.Contains(n) && !closed.Contains(n)) {
                        n.gCost = cost;
                        n.hCost = heuristic(n, Target);
                        n.parent = current;
                        open.Add(n);
                    }
                }
            }

        // no path available
        return new List<GridNode>();
        }
    }
}
```

LocationLocator.cs

```csharp
using System;
using System.Collections.Generic;
using System.Linq;
using System.Text;
```

```
namespace GridWorld
{
    class LocationLocator
    {

        private Cell[,] localMap;
        private int id;

        private Tuple<int, int> unexplored;

        /// <summary>
        /// Constructs the class.
        /// </summary>
        /// <param name="localMap">Map of the game environment.</param>
        /// <param name="id">The ID of the player.</param>
        public LocationLocator(Cell[,] localMap,  int id)
        {
            this.unexplored = null;
            Update(localMap, id);
        }

        /// <summary>
        /// Updates the localMap
        /// </summary>
        /// <param name="localMap">Map of the game environment.</param>
        /// <param name="id">The ID of the player.</param>
        public void Update(Cell[,] localMap,  int id)
        {
            this.localMap = localMap;
            this.id = id;
        }

        /// <summary>
        /// Gives a location to locate to.
        /// </summary>
        /// <param name="threat">The threat to retreat from.</param>
        /// <param name="hero">The player</param>
        /// <returns>A Tuple with the coordinates of the destination.</returns>
        public Tuple<int, int> Retreat(GridSquare threat, GridSquare hero)
        {
            int mapWidth = localMap.GetLength(0);
            int mapHeigth = localMap.GetLength(1);

            int searchSize = 1;
            List<GridNode> obs = MapObs(searchSize, hero);

            while(obs.Count == 0)
            {
                if (searchSize < 3)
                {
```

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```
            searchSize++;
            obs = MapObs(searchSize, hero);
        }
        else
            return RandomDodge(mapWidth, mapHeigth, threat, hero);
    }

    foreach (GridNode gn in obs)
    {
        if (gn.y == hero.Y && SimpleDodgeX(gn.x, gn.y, hero.X).Item1 != -1)
            return SimpleDodgeX(gn.x, gn.y, hero.X);
        else if (gn.x == hero.X && SimpleDodgeY(gn.y, gn.x, hero.Y).Item1
            ↪ != -1)
            return SimpleDodgeY(gn.y, gn.x, hero.Y);
        else if (gn.y > hero.Y)
        {
            if (gn.y < mapWidth)
                if (localMap[gn.x, gn.y + 1] == Cell.Empty)
                    return new Tuple<int, int>(gn.x, gn.y + 1);
                else if (AdvancedDodge(gn, hero).Item1 != -1)
                    return AdvancedDodge(gn, hero);
        }
        else if (gn.y < hero.Y)
        {
            if (gn.y > 0)
                if (localMap[gn.x, gn.y - 1] == Cell.Empty)
                    return new Tuple<int, int>(gn.x, gn.y + 1);
                else if (AdvancedDodge(gn, hero).Item1 != -1)
                    return AdvancedDodge(gn, hero);
        }
    }

    return RandomDodge(mapWidth, mapHeigth, threat, hero);
}

/// <summary>
/// Dodges behind a rock in one of the two cardinal X directions.
/// </summary>
/// <param name="gnMain">The axis shared with the Hero.</param>
/// <param name="gnSec">The axis not shared with the Hero.</param>
/// <param name="hMain">The Hero coord on the shared axis.</param>
/// <returns>A Tuple to move to. Will contain -1, -1 if not valid.</returns
    ↪ >
private Tuple<int, int> SimpleDodgeX(int gnMain, int gnSec, int hMain)
{
    if (gnMain < hMain && gnMain > 0)
        if (localMap[gnMain - 1, gnSec] == Cell.Empty)
            return new Tuple<int, int>(gnMain - 1, gnSec);
    if (gnMain > hMain && gnMain < localMap.GetLength(0))
        if (localMap[gnMain + 1, gnSec] == Cell.Empty)
            return new Tuple<int, int>(gnMain + 1, gnSec);
```

```
        return new Tuple<int, int>(-1, -1);
}


/// <summary>
/// Dodges behind a rock in one of the two cardinal Y directions.
/// </summary>
/// <param name="gnMain">The axis shared with the Hero.</param>
/// <param name="gnSec">The axis not shared with the Hero.</param>
/// <param name="hMain">The Hero coord on the shared axis.</param>
/// <returns>A Tuple to move to. Will contain -1, -1 if not valid.</returns
    ↪ >
private Tuple<int, int> SimpleDodgeY(int gnMain, int gnSec, int hMain)
{
    if (gnMain < hMain && gnMain > 0)
        if (localMap[gnSec, gnMain - 1] == Cell.Empty)
            return new Tuple<int, int>(gnSec, gnMain - 1);
    if (gnMain > hMain && gnMain < localMap.GetLength(1))
        if (localMap[gnSec, gnMain + 1] == Cell.Empty)
            return new Tuple<int, int>(gnSec, gnMain + 1);

    return new Tuple<int, int>(-1, -1);
}


/// <summary>
/// Checks if cover either above or below the player can be hidden behind
    ↪ on the X-axis.
/// </summary>
/// <param name="gn">The GridNode to hide behind.</param>
/// <param name="hero">The player location</param>
/// <returns>A Tuple to move to. Will contain -1, -1 if not valid.</returns
    ↪ >
private Tuple<int, int> AdvancedDodge(GridNode gn, GridSquare hero)
{
    if (gn.x > hero.X)
    {
        if (gn.x < localMap.GetLength(0))
            if (localMap[gn.x + 1, gn.y] == Cell.Empty)
                return new Tuple<int, int>(gn.x + 1, gn.y);
    }
    else if (gn.x < hero.X)
    {
        if (gn.x > 0)
            if (localMap[gn.x - 1, gn.y] == Cell.Empty)
                return new Tuple<int, int>(gn.x - 1, gn.y);
    }

    return new Tuple<int, int>(-1, -1);
}

/// <summary>
```

```csharp
/// Maps the obstacles surronding the player.
/// </summary>
/// <param name="size">How far away from the player to go.</param>
/// <param name="hero">The player location</param>
/// <returns>A list of the nearby obstacles.</returns>
private List<GridNode> MapObs(int size, GridSquare hero)
{
    List<GridNode> obs = new List<GridNode>();

    for (int i = hero.X - size; i <= hero.X + size; i++)
    {
        for (int j = hero.Y - size; j <= hero.Y + size; j++)
        {
            if(IsValidCoordinate(new Tuple<int, int>(i, j)))
                if (localMap[i, j] == Cell.Rock)
                    obs.Add(new GridNode(i, j, Cell.Rock));
        }
    }
    return obs;
}


/// <summary>
/// Dodges randomly when no hiding place can be found.
/// </summary>
/// <param name="w">The width of the board.</param>
/// <param name="h">The height of the board.</param>
/// <param name="t">The target to escape from.</param>
/// <param name="hero">The player location</param>
/// <returns>A Tuple with the coordinates of the destination.</returns>
private Tuple<int, int> RandomDodge(int w, int h, GridSquare t, GridSquare
    ↪ hero)
{
    Random r = new Random();

    int xDiff;
    if(hero.X > t.X)
        xDiff = Math.Abs(hero.X - t.X);
    else
        xDiff = Math.Abs(t.X - hero.X);

    int yDiff;
    if (hero.Y > t.Y)
        yDiff = Math.Abs(hero.Y - t.Y);
    else
        yDiff = Math.Abs(t.Y - hero.Y);

    if (xDiff < yDiff)          //Closer on the x-axis, dodge vertically
        return Dodge(0, 1, hero);
    else                        //Closer on the y-axis, dodge horizontally
        return Dodge(1, 0, hero);
}
```

```csharp
/// <summary>
/// Determines where to dodge.
/// </summary>
/// <param name="xAdd">How far to look in the X-direction.</param>
/// <param name="yAdd">How far to look in the Y-direction.</param>
/// <param name="hero">The player location.</param>
/// <returns>A Tuple with the coordinates of the destination.</returns>
private Tuple<int, int> Dodge(int xAdd, int yAdd, GridSquare hero)
{
    Random r = new Random();
    if (localMap[hero.X + xAdd, hero.Y + yAdd] != Cell.Rock && localMap[
        ↪ hero.X - xAdd, hero.Y - yAdd] != Cell.Rock && localMap[hero.X +
        ↪ xAdd, hero.Y + yAdd] != Cell.Destroyed && localMap[hero.X - xAdd,
        ↪  hero.Y - yAdd] != Cell.Destroyed)
    {
        if (r.Next(2) == 0)
            return new Tuple<int, int>(hero.X + xAdd, hero.Y + yAdd);
        else
            return new Tuple<int, int>(hero.X - xAdd, hero.Y - yAdd);
    }
    if (localMap[hero.X - xAdd, hero.Y - yAdd] != Cell.Rock && localMap[
        ↪ hero.X - xAdd, hero.Y - yAdd] != Cell.Destroyed)
        return new Tuple<int, int>(hero.X - xAdd, hero.Y - yAdd);
    if (localMap[hero.X + xAdd, hero.Y + yAdd] != Cell.Rock && localMap[
        ↪ hero.X + xAdd, hero.Y + yAdd] != Cell.Destroyed)
        return new Tuple<int, int>(hero.X + xAdd, hero.Y + yAdd);

    return RandomKnown(localMap.GetLength(0), localMap.GetLength(1));
}


/// <summary>
/// Makes a decision how to attack.
/// </summary>
/// <param name="threat">The enemy to attack</param>
/// <param name="facing">The direction the player is facing.</param>
/// <param name="toEnemy">The pathfinder.</param>
/// <param name="hero">The player location</param>
/// <returns>The issued command.</returns>
public Command Attack(GridSquare threat, PlayerWorldState.Facing facing,
    ↪ Command toEnemy, GridSquare hero)
{
    if (hero.X == threat.X)
    {
        if (hero.Y > threat.Y)
            return AttackFacing(facing, PlayerWorldState.Facing.Down,
                ↪ PlayerWorldState.Facing.Right, PlayerWorldState.Facing.
                ↪ Left);
        else if (hero.Y < threat.Y)
            return AttackFacing(facing, PlayerWorldState.Facing.Up,
                ↪ PlayerWorldState.Facing.Left, PlayerWorldState.Facing.
```

```
            ↪ Right);
    }
    else if(hero.Y == threat.Y)
    {
        if (hero.X > threat.X)
            return AttackFacing(facing, PlayerWorldState.Facing.Left,
                ↪ PlayerWorldState.Facing.Down, PlayerWorldState.Facing.Up)
                ↪ ;
        else if (hero.X < threat.X)
            return AttackFacing(facing, PlayerWorldState.Facing.Right,
                ↪ PlayerWorldState.Facing.Up, PlayerWorldState.Facing.Down)
                ↪ ;
    }

    return toEnemy;

}

/// <summary>
/// Attacks if the player is facing an opponent.
/// </summary>
/// <param name="facing">The direction the player is facing.</param>
/// <param name="noRotate">The direction to face when facing the enemy.</
    ↪ param>
/// <param name="rotateRight">The direction to face when one rotateRight
    ↪ away from the enemy.</param>
/// <param name="rotateLeft">The direction to face when one rotateLeft away
    ↪  from the enemy.</param>
/// <returns>A command to execute.</returns>
private Command AttackFacing(PlayerWorldState.Facing facing,
    ↪ PlayerWorldState.Facing noRotate, PlayerWorldState.Facing rotateRight
    ↪ , PlayerWorldState.Facing rotateLeft)
{
    if (facing == noRotate)
        return new Command(Command.Move.Down, true);
    else if (facing == rotateRight)
        return new Command(Command.Move.RotateRight, true);
    else if (facing == rotateLeft)
        return new Command(Command.Move.RotateLeft, true);
    else
        return new Command(Command.Move.RotateLeft, false);
}

/// <summary>
/// Gives a random known node to path to.
/// </summary>
/// <param name="w">The width of the board.</param>
/// <param name="h">The height of the board.</param>
/// <returns>A Tuple with the coordinates of the destination.</returns>
public Tuple<int, int> RandomKnown(int w, int h)
{
```

```csharp
        Random r = new Random();
        Cell c;
        int x;
        int y;
        do
        {
            x = r.Next(w);
            y = r.Next(h);
            c = localMap[w, h];
        } while (c != Cell.Empty);

        return new Tuple<int, int>(x, y);
    }


    /// <summary>
    /// Find a random cell that we can reach from our current position.
    /// </summary>
    /// <param name="hero">Our current position.</param>
    /// <returns>A reachable cell.</returns>
    public Tuple<int, int> RandomReachable(GridSquare hero)
    {
        List<Tuple<int, int>> reachableCells = ReachableUnexplored(hero);

        for (int x = 0; x < localMap.GetLength(0); x++)
        {
            for (int y = 0; y < localMap.GetLength(1); y++)
            {
                if ((localMap[x, y] == Cell.Empty || localMap[x, y] == Cell.
                    ↪ Hero) // to account for possibly not cleaning Hero right
                    && (x != hero.X && y != hero.Y))
                {
                    reachableCells.Add(new Tuple<int, int>(x, y));
                }
            }
        }

        Random r = new Random();
        return reachableCells.ElementAt(r.Next(reachableCells.Count));
    }


    /// <summary>
    /// Refresh the current target unexplored location. Needed in case our path
    ///    ↪  gets blocked off.
    /// </summary>
    public void RefreshUnexplored()
    {
        unexplored = null;
    }


    /// <summary>
    /// Return an unexplored node reachable from our current position.
```

```
/// The node is cached until it ceases being unexplored or is refreshed,
/// to ensure consistency.
/// </summary>
/// <param name="hero">Our current position.</param>
/// <returns>A reachable unexplored node.</returns>
public Tuple<int, int> UnexploredNode(GridSquare hero)
{
    if (unexplored == null)
    {
        SetUnexploredNode(hero); // potential for infinite loop if called
            ↪ with no unexplored nodes remaining
    }

    if (localMap[unexplored.Item1, unexplored.Item2] != Cell.Unexplored)
    {
        SetUnexploredNode(hero);
    }

    return unexplored;
}


/// <summary>
/// Find a random unexplored node that is reachable (i.e. 'pathfindable'
///     ↪ from our
/// current position) and set it as the current "unexplored" target.
/// </summary>
/// <param name="hero">The player's position</param>
private void SetUnexploredNode(GridSquare hero)
{
    List<Tuple<int, int>> unexplored = ReachableUnexplored(hero);

    if (unexplored.Count == 0)
    {
        this.unexplored = null;
    }

    Random r = new Random();
    this.unexplored = unexplored.ElementAt(r.Next(unexplored.Count));
}


/// <summary>
/// Determine all unexplored nodes reachable from our current position.
/// </summary>
/// <param name="hero">Our current position.</param>
/// <returns>A list of all reachable unexplored nodes.</returns>
private List<Tuple<int, int>> ReachableUnexplored(GridSquare hero)
{
    List<Tuple<int, int>> checkedList = new List<Tuple<int, int>>();
    List<Tuple<int, int>> unexplored = new List<Tuple<int, int>>();
    Stack<Tuple<int, int>> toCheck = new Stack<Tuple<int, int>>();
```

```csharp
        Tuple<int, int> start = new Tuple<int, int>(hero.X, hero.Y);
        toCheck.Push(start);
        while (toCheck.Count != 0)
        {
            Tuple<int, int> current = toCheck.Pop();

            if (checkedList.Contains(current))
            {
                continue;
            }

            if (unexplored.Contains(current))
            {
                continue;
            }

            if (localMap[current.Item1, current.Item2] != Cell.Unexplored)
            {
                checkedList.Add(current);
            }
            else
            {
                unexplored.Add(current);
            }

            List<Tuple<int, int>> neightbours = GetNodeNeighbours(current);

            foreach (Tuple<int, int> cell in neightbours)
            {
                if (!(checkedList.Contains(cell))
                    && !(unexplored.Contains(cell)))
                {
                    toCheck.Push(cell);
                }
            }
        }

        return unexplored;
}

/// <summary>
/// Find all the neightbours of a given node, IF that node is not
///     unexplored
/// or a rock. (This method needs refining!)
/// </summary>
/// <param name="node">Coodrinates of a node to start from</param>
/// <returns>All neighbours of a non-unexplored node</returns>
private List<Tuple<int, int>> GetNodeNeighbours(Tuple<int, int> node)
{
    List<Tuple<int, int>> neighbours = new List<Tuple<int, int>>();
```

```
    //if (localMap[node.Item1, node.Item2] != Cell.Unexplored
    // && localMap[node.Item1, node.Item2] != Cell.Rock)
    if(!potentialWall(node))
    {
        Stack<Tuple<int, int>> potentialNeighbours
            = new Stack<Tuple<int, int>>();

        int x = node.Item1;
        int y = node.Item2;

        potentialNeighbours.Push(new Tuple<int, int>(x+1, y));
        potentialNeighbours.Push(new Tuple<int, int>(x-1, y));
        potentialNeighbours.Push(new Tuple<int, int>(x, y+1));
        potentialNeighbours.Push(new Tuple<int, int>(x, y-1));

        foreach (Tuple<int, int> coor in potentialNeighbours)
        {
            if (IsValidCoordinate(coor))
            {
                neighbours.Add(coor);
            }
        }
    }

    return neighbours;
}


/// <summary>
/// Determine whether a block is likely to belong to a "wall" that we can't
///    ↪ pathfind around.
/// </summary>
/// <param name="coord">Coodrinates of a node to check</param>
/// <returns>True if coord is a potential element in the middle of a wall,
///    ↪ false if it is a passable node or possibly a wall "edge".</returns>
private bool potentialWall(Tuple<int, int> coord)
{
    if (passable(coord))
    {
        return false;
    }

    Stack<Tuple<int, int>> leftRight = new Stack<Tuple<int, int>>();
    List<Tuple<int, int>> leftRightValid = new List<Tuple<int, int>>();
    Stack<Tuple<int, int>> upDown = new Stack<Tuple<int, int>>();
    List<Tuple<int, int>> upDownValid = new List<Tuple<int, int>>();

    int x = coord.Item1;
    int y = coord.Item2;

    leftRight.Push(new Tuple<int, int>(x - 1, y));
    leftRight.Push(new Tuple<int, int>(x + 1, y));
```

```
        upDown.Push(new Tuple<int, int>(x, y + 1));
        upDown.Push(new Tuple<int, int>(x, y - 1));

        bool result = true;

        foreach (var coor in leftRight)
        {
            if (IsValidCoordinate(coor))
            {
                result &= nonObsticle(coor);
            }
        }

        if (result)
        {
            return true;
        }

        result = true;

        foreach (Tuple<int, int> coor in upDown)
        {
            if (IsValidCoordinate(coor))
            {
                result &= nonObsticle(coor);
            }
        }

        return result;
    }

    /// <summary>
    /// Checks if a given node is traversable in terms of pathfinding
    /// </summary>
    /// <param name="coord">Coordinates of a node to check</param>
    /// <returns>True if pathfinding considers the node passable, false
    ///     ↪ otherwise.</returns>
    private bool passable(Tuple<int, int> coord)
    {
        return (localMap[coord.Item1, coord.Item2] == Cell.Empty)
            || (localMap[coord.Item1, coord.Item2] == Cell.Hero);
    }

    /// <summary>
    /// Check if a map is not an obsticle. Since this is used for exploring the
    ///     ↪  map, we consider Unexplored
    /// cells to not be obsticles. Please keep in mind that this should ONLY be
    ///     ↪  used when analyzing a cell
    /// as belonging to a wall or not. A rock with an unexplored cell above it
    ///     ↪ is considered to be at the
```

```
/// "edge", since we don't know if the Unexplored cell is passable or not.
    ↪ However, neighbours of such
/// cells should not be generated, as that would lead to the whole map
    ↪ being considered reachable.
/// </summary>
/// <param name="coord">Coordinates of a node to check</param>
/// <returns>See method description</returns>
private bool nonObsticle(Tuple<int, int> coord)
{
    return passable(coord) || (localMap[coord.Item1, coord.Item2] == Cell.
        ↪ Unexplored);
}


/// <summary>
/// Check if a coordinate is within the bounds of the current map
/// </summary>
/// <param name="coor">Coordinate to be checked</param>
/// <returns>True if coordinate is a valid index into the map array</
    ↪ returns>
private bool IsValidCoordinate(Tuple<int, int> coor)
{
    if (coor.Item1 < 0 || coor.Item2 < 0)
    {
        return false;
    }

    if (coor.Item1 > localMap.GetLength(0) - 1
      || coor.Item2 > localMap.GetLength(1) - 1)
    {
        return false;
    }

    return true;
}
    }
}
```

AI.cs