

RS-HL-14: Multi User Congestion Game

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Configuration of Congestion Game

Algorithm for C

I. Load the Dataset

```
clear;clc;
% Load the Satellite Contat Dataset
addpath( '~/Desktop/Redstone_Project/RS_HL/RS_HL_10_TV_MDP_Functions' )
load( '/workspace/RS_Dataset/RS_HL_3_dataset.mat' )
```

II. Destination Setting and Time Index Vector Setting

```
time_index_vector = 100:130;
start_time_index = 100:120;

number_of_agents = 100;
number_of_destinations = 5;
state_vector = 1:48;

start_state = state_vector(randi(numel(state_vector), 1, number_of_agents));
destination_values = randsample(state_vector,number_of_destinations);
destination_state = destination_values(randi(numel(destination_values), 1,
number_of_agents));
start_time = start_time_index(randi(numel(start_time_index), 1,
number_of_agents));
```

II.1 Run the MDP simulation for each destination

```
fprintf('Total Number of Destinations: %d\n', number_of_destinations);
```

Total Number of Destinations: 5

```
for destination_index = 1:number_of_destinations
    fprintf('-----\n')
```

```

    fprintf('Running MDP %d / %d , Destination %d \n',
destination_index,number_of_destinations,destination_values(destination_index
));
    MDP.(['MDP', num2str(destination_values(destination_index))])
= runMDP(sat_to_sat_contact_3d_matrix,
time_index_vector,destination_values(destination_index));

end

```

```

-----
Running MDP 1 / 5 , Destination 35
simulation set up complete!
Policy: 1 -> Value Iteration: 418
Policy: 2 -> Value Iteration: 14
Policy: 3 -> Value Iteration: 7
Policy: 4 -> Value Iteration: 5
Policy: 5 -> Value Iteration: 6
Policy: 6 -> Value Iteration: 11
Policy: 7 -> Value Iteration: 5
Policy: 8 -> Value Iteration: 1

```

```

-----
Running MDP 2 / 5 , Destination 32
simulation set up complete!
Policy: 1 -> Value Iteration: 419
Policy: 2 -> Value Iteration: 13
Policy: 3 -> Value Iteration: 7
Policy: 4 -> Value Iteration: 5
Policy: 5 -> Value Iteration: 6
Policy: 6 -> Value Iteration: 10
Policy: 7 -> Value Iteration: 5
Policy: 8 -> Value Iteration: 5
Policy: 9 -> Value Iteration: 1

```

```

-----
Running MDP 3 / 5 , Destination 20
simulation set up complete!
Policy: 1 -> Value Iteration: 460
Policy: 2 -> Value Iteration: 14
Policy: 3 -> Value Iteration: 5
Policy: 4 -> Value Iteration: 5
Policy: 5 -> Value Iteration: 5
Policy: 6 -> Value Iteration: 11
Policy: 7 -> Value Iteration: 4
Policy: 8 -> Value Iteration: 5
Policy: 9 -> Value Iteration: 1
Policy: 10 -> Value Iteration: 1
Policy: 11 -> Value Iteration: 1
Policy: 12 -> Value Iteration: 1
Policy: 13 -> Value Iteration: 1
Policy: 14 -> Value Iteration: 1
Policy: 15 -> Value Iteration: 1

```

```

-----
Running MDP 4 / 5 , Destination 40
simulation set up complete!
Policy: 1 -> Value Iteration: 441
Policy: 2 -> Value Iteration: 14
Policy: 3 -> Value Iteration: 6
Policy: 4 -> Value Iteration: 5
Policy: 5 -> Value Iteration: 8
Policy: 6 -> Value Iteration: 10
Policy: 7 -> Value Iteration: 9
Policy: 8 -> Value Iteration: 1
Policy: 9 -> Value Iteration: 1

```

```

-----
Running MDP 5 / 5 , Destination 47
simulation set up complete!
Policy: 1 -> Value Iteration: 434
Policy: 2 -> Value Iteration: 14
Policy: 3 -> Value Iteration: 7
Policy: 4 -> Value Iteration: 5
Policy: 5 -> Value Iteration: 7
Policy: 6 -> Value Iteration: 9
Policy: 7 -> Value Iteration: 5
Policy: 8 -> Value Iteration: 1

```

```
fprintf('-----\n')
```

III. Configure each Agent's Setting

```
agents_input = [start_time', start_state', destination_state'];
```

IV. Configure the simulation structure setting

```

% Level 1: Initialize simulation structure
sim = struct();

for time_index = time_index_vector
    sim.(['time' num2str(time_index)]) = {};
end

% Level 2/3: Initialize Agent (Level 2) with States and Destination (Level 3)

number_of_agents = length(agents_input(:,1));

for agent_index = 1:number_of_agents
    sim.(['time' num2str(agents_input(agent_index,1))]).(['agent'
num2str(agent_index)]).('state') = agents_input(agent_index,2);
    sim.(['time' num2str(agents_input(agent_index,1))]).(['agent'
num2str(agent_index)]).('destination') = agents_input(agent_index,3);
end

```

V. Configuration of Action Value Structure and Simulation Structure

```

% Initialize Action Value Structure
action_value_struct = struct();

```

```

for time_index = time_index_vector

    % If there's no active agent, continue to next time step
    if isempty(sim.(['time' num2str(time_index)]))
        continue;
    end

    % Parse the number of active agents
    number_of_active_agents = length(fieldnames(sim.(['time'
num2str(time_index)])));

    % Make the status matrix represents current and next
    % [current_state, next_state, destination]
    status_matrix = zeros(3, number_of_active_agents);

    agents_list = fieldnames(sim.(['time' num2str(time_index)]));

    % Definine Original Policy Distribution Matrix
    original_policy_matrix =
zeros(number_of_active_agents,length(state_vector));

    % Find the Next state from Current Agent-State
    for active_agent_index = 1:number_of_active_agents
        % Find the Current State and Destination of given agent
        current_state = sim.(['time' num2str(time_index)]).
(agents_list{active_agent_index}).('state');
        destination = sim.(['time' num2str(time_index)]).
(agents_list{active_agent_index}).('destination');

        % Get the Action values and corresponding next states from given
state in given MDP
        action_value_vector = MDP.(['MDP' num2str(destination)]).
(['time' num2str(time_index)]).(['state' num2str(current_state)]).
('action_value_vector');
        next_state_vector = MDP.(['MDP' num2str(destination)]).
(['time' num2str(time_index)]).(['state' num2str(current_state)]).
('next_state_vector');

        % Action Value Matrix Config: [Action index, Action Value Q, Next
State S']
        vector_length = length(action_value_vector);
        action_value_matrix = [(1:vector_length)',action_value_vector,
next_state_vector, action_value_vector];
        action_value_matrix = sortrows(action_value_matrix,2, 'descend');
        action_value_struct.(['time' num2str(time_index)]).
(agents_list{active_agent_index}).('action_value_matrix') =
action_value_matrix;

```

```

    % Find the Active Actoin Number from given Original MDP pi
distribution
    pi_dist = MDP.(['MDP' num2str(destination)]).(['time'
num2str(time_index)]).('policy_distribution');
    action_number = find(pi_dist(current_state,:) ~= 0);

    for action_number_index = 1:length(action_number)

original_policy_matrix(active_agent_index,action_number(action_number_index))
    = action_number(action_number_index);
        end

    % Get Activated Next States Vector (Which is from pi distribution)
    activated_next_states = action_number;
    action_value_struct.(['time' num2str(time_index)]).
(agents_list{active_agent_index}).('activated_next_states') =
activated_next_states;

    if length(action_number) > 1
        action_number = randsample(action_number,1);
    end

    next_state = MDP.(['MDP' num2str(destination)]).(['time'
num2str(time_index)]).(['state' num2str(current_state)]).(['action'
num2str(action_number)]).('success').('next_state');
    reward = MDP.(['MDP' num2str(destination)]).(['time'
num2str(time_index)]).(['state' num2str(current_state)]).(['action'
num2str(action_number)]).('success').('reward');
    state_value = MDP.(['MDP' num2str(destination)]).(['time'
num2str(time_index)]).(['state' num2str(current_state)]).('state_value');
    action_value = MDP.(['MDP' num2str(destination)]).
(['time' num2str(time_index)]).(['state' num2str(current_state)]).(['action'
num2str(action_number)]).('action_value');

    % Configure Proposed status matrix for the collision test
    status_matrix(1,active_agent_index) = current_state;
    status_matrix(2,active_agent_index) = next_state;
    status_matrix(3,active_agent_index) = destination;

    % Add State Value
    sim.(['time' num2str(time_index)]). (agents_list{active_agent_index}).
('state_value') = state_value;

    % Save the Original Reward and action value to prepare the update
    sim.(['time' num2str(time_index)]). (agents_list{active_agent_index}).
('original_action_number') = action_number;
    sim.(['time' num2str(time_index)]). (agents_list{active_agent_index}).
('original_action_value') = action_value;
    sim.(['time' num2str(time_index)]). (agents_list{active_agent_index}).
('original_reward') = reward;

```

```

        sim.(['time' num2str(time_index)]).(agents_list{active_agent_index}).
('original_next_state') = next_state;

        % Add the action number, reward, action value (may be changed)
        sim.(['time' num2str(time_index)]).(agents_list{active_agent_index}).
('action_number') = action_number;
        sim.(['time' num2str(time_index)]).(agents_list{active_agent_index}).
('action_value') = action_value;
        sim.(['time' num2str(time_index)]).(agents_list{active_agent_index}).
('reward') = reward;
        sim.(['time' num2str(time_index)]).(agents_list{active_agent_index}).
('next_state') = next_state;
    end

```

V.1 Policy Iteration By Updating Q values of potential Collision by given policy distribution

```

    updated_policy_matrix =
zeros(number_of_active_agents,length(state_vector));
    policy_iteration = 0;
    congestion_cost_factor = 12;

    while true
        % while isequal(original_policy_matrix,updated_policy_matrix) == false
        policy_iteration = policy_iteration + 1;

        if policy_iteration > 1
            original_policy_matrix = updated_policy_matrix;
        end

        for active_agent_index = 1:number_of_active_agents

            action_value_matrix = action_value_struct.
(['time' num2str(time_index)]).(agents_list{active_agent_index}).
('action_value_matrix');
            action_value_matrix_original = action_value_matrix;

            number_of_actions = length(action_value_matrix(:,1));

            for test_agent_index = 1:number_of_active_agents
                if active_agent_index == test_agent_index
                    continue;
                end
            end
        end
    end

```

```

        index_starting_next_timestep = find(agents_input(:,1) ==
time_index+1);
        agents_input_extracted =
agents_input(index_starting_next_timestep,:);

        starting_state_list = agents_input_extracted(:,2)';

        test_activated_next_index =
original_policy_matrix(active_agent_index);
        text_activated_next_states =
test_activated_next_index(test_activated_next_index ~= 0);
        % test_activated_next_states
= action_value_struct.(['time' num2str(time_index)]).
(agents_list{test_agent_index}).('activated_next_states');
        test_activated_states = [text_activated_next_states,
starting_state_list];

        for action_index = 1:number_of_actions
            action_value_mat_next_state =
action_value_matrix(action_index,3);
            congestion_indicator = length(find(test_activated_states ==
action_value_mat_next_state));
            current_action_value = action_value_matrix(action_index,2);
            updated_action_value = current_action_value -
congestion_cost_factor * congestion_indicator;
            action_value_matrix(action_index,4) = updated_action_value;
        end
    end
    % if isequal(action_value_matrix(:,1),
action_value_matrix_updated(:,1)) == false
    %     fprintf('there was correctance \n')
    % end

    action_value_struct.(['time' num2str(time_index)]).
(agents_list{active_agent_index}).('action_value_matrix') =
action_value_matrix;

    % Policy Iteration Process -> Should Be Done

end

% Update The Action Number

for active_agent_index = 1:number_of_active_agents
    % Find the Current State and Destination of given agent
    current_state = sim.(['time' num2str(time_index)]).
(agents_list{active_agent_index}).('state');

```

```

        destination = sim.(['time' num2str(time_index)]).
(agents_list{active_agent_index}).('destination');

        % if current_state == destination
        %     continue;
        % end

        action_value_matrix = action_value_struct.
(['time' num2str(time_index)]).(agents_list{active_agent_index}).
('action_value_matrix');
        updated_action_value_vector = max(action_value_matrix(:,4));
        updated_action_index = find(updated_action_value_vector ==
action_value_matrix(:,4));
        updated_action_policy = action_value_matrix(updated_action_index,1);

        for index = 1:length(updated_action_policy)
            updated_policy_matrix(active_agent_index,
updated_action_policy(index)) = updated_action_policy(index);
        end

        % Get Activated Next States Vector (Which is from pi distribution)
        activated_next_states_updated =
updated_policy_matrix(active_agent_index,:);
        activated_next_states_updated =
activated_next_states_updated(activated_next_states_updated ~= 0)';
        action_value_struct.(['time' num2str(time_index)]).
(agents_list{active_agent_index}).('activated_next_states') =
activated_next_states_updated';

        if length(updated_action_index) > 1
            updated_action_index = randsample(updated_action_index,1);
        end

        action_number = action_value_matrix(updated_action_index,1);
        action_value = action_value_matrix(updated_action_index,2);
        next_state = action_value_matrix(updated_action_index,3);
        reward = MDP.(['MDP' num2str(destination)]).(['time'
num2str(time_index)]).(['state' num2str(current_state)]).(['action'
num2str(action_number)]).('success').('reward');

        % Modify Proposed status matrix for the collision test
        status_matrix(1,active_agent_index) = current_state;
        status_matrix(2,active_agent_index) = next_state;
        status_matrix(3,active_agent_index) = destination;

        % Modify the action number, reward, action value (may be changed)
        sim.(['time' num2str(time_index)]).(agents_list{active_agent_index}).
('action_number') = action_number;

```



```

        sim.(['time' num2str(time_index)]).(agents_list{active_agent_index}).
('action_value') = action_value;
        sim.(['time' num2str(time_index)]).(agents_list{active_agent_index}).
('reward') = reward;
        sim.(['time' num2str(time_index)]).(agents_list{active_agent_index}).
('next_state') = next_state;

        % original_action_number = sim.(['time' num2str(time_index)]).
(agents_list{active_agent_index}).('original_action_number');
        % Check the Update of the values
        % if isequal(action_number, original_action_number) == false
        %     fprintf('action_number changed from %d to %d
\n',original_action_number,action_number)
        %     time_index
        %     agents_list{active_agent_index}
        %     sim.(['time' num2str(time_index)]).
(agents_list{active_agent_index})
        % end

    end

    if isequal(original_policy_matrix,updated_policy_matrix) == true
    break;
    end
end

fprintf('Policy Iteration Completed at time %d by %d iterations
\n',time_index, policy_iteration)

```

V.1 Propagation With Randomness

```

% Break when time index reaches the end time
if time_index == max(time_index_vector)
    break;
end

% Actual Propagation of The State by Time

for active_agent_index = 1:number_of_active_agents

% Generate Random Factor
random_factor = rand(1,1);

% Call the Current State, Destination, and Action Number of given agent

```

```

        current_state = sim(['time' num2str(time_index)]).
(agents_list{active_agent_index}).('state');
        destination = sim(['time' num2str(time_index)]).
(agents_list{active_agent_index}).('destination');
        action_number = sim(['time' num2str(time_index)]).
(agents_list{active_agent_index}).('action_number');

        transmission_probability = MDP(['MDP' num2str(destination)]).
(['time' num2str(time_index)]).(['state' num2str(current_state)]).(['action'
num2str(action_number)]).('success').('transition_probability');
        if random_factor > -1
            % if random_factor > 1 - transmission_probability
            % Update the time+1 for next state

            % Don't update the agent already arrived to destination
            if current_state == destination
                continue;
            end

            sim(['time' num2str(time_index+1)]).
(agents_list{active_agent_index}).('state') =
status_matrix(2,active_agent_index);
            sim(['time' num2str(time_index+1)]).
(agents_list{active_agent_index}).('destination') =
status_matrix(3,active_agent_index);

        else
            sim(['time' num2str(time_index+1)]).
(agents_list{active_agent_index}).('state') = current_state;
            sim(['time' num2str(time_index+1)]).
(agents_list{active_agent_index}).('destination') =
status_matrix(3,active_agent_index);
            % Since it is failure, we should replace reward as failure
penalty
            failure_reward = MDP(['MDP' num2str(destination)]).
(['time' num2str(time_index)]).(['state' num2str(current_state)]).(['action'
num2str(action_number)]).('fail').('reward');
            sim(['time' num2str(time_index)]).
(agents_list{active_agent_index}).('reward') = failure_reward;
        end
    end
end
end

```

```

Policy Iteration Completed at time 100 by 1 iterations
Policy Iteration Completed at time 101 by 2 iterations
Policy Iteration Completed at time 102 by 1 iterations
Policy Iteration Completed at time 103 by 2 iterations
Policy Iteration Completed at time 104 by 2 iterations
Policy Iteration Completed at time 105 by 2 iterations
Policy Iteration Completed at time 106 by 2 iterations
Policy Iteration Completed at time 107 by 2 iterations

```

```

Policy Iteration Completed at time 108 by 2 iterations
Policy Iteration Completed at time 109 by 2 iterations
Policy Iteration Completed at time 110 by 2 iterations
Policy Iteration Completed at time 111 by 2 iterations
Policy Iteration Completed at time 112 by 1 iterations
Policy Iteration Completed at time 113 by 2 iterations
Policy Iteration Completed at time 114 by 2 iterations
Policy Iteration Completed at time 115 by 2 iterations
Policy Iteration Completed at time 116 by 2 iterations
Policy Iteration Completed at time 117 by 2 iterations
Policy Iteration Completed at time 118 by 2 iterations
Policy Iteration Completed at time 119 by 2 iterations
Policy Iteration Completed at time 120 by 1 iterations
Policy Iteration Completed at time 121 by 1 iterations
Policy Iteration Completed at time 122 by 1 iterations
Policy Iteration Completed at time 123 by 1 iterations
Policy Iteration Completed at time 124 by 1 iterations
Policy Iteration Completed at time 125 by 1 iterations
Policy Iteration Completed at time 126 by 1 iterations
Policy Iteration Completed at time 127 by 1 iterations
Policy Iteration Completed at time 128 by 1 iterations
Policy Iteration Completed at time 129 by 1 iterations
Policy Iteration Completed at time 130 by 1 iterations

```

VI. result display

```

result_matrix = zeros(length(time_index_vector),number_of_agents);
reward_matrix = zeros(length(time_index_vector),number_of_agents);
state_value_matrix = zeros(length(time_index_vector),number_of_agents);
action_value_matrix = zeros(length(time_index_vector),number_of_agents);
cumulative_reward_matrix = zeros(length(time_index_vector),number_of_agents);

for time_index = time_index_vector

    if isempty(sim.(['time' num2str(time_index)]))
        continue;
    end

    agents_list = fieldnames(sim.(['time' num2str(time_index)]));
    number_of_agents = length(agents_list);

    for agent_index = 1:number_of_agents
        agent_name = cell2mat(agents_list(agent_index));
        agent_no = regexp(agent_name, '\d+', 'match');
        agent_number = str2double(agent_no{1});

        result_matrix(time_index - min(time_index_vector) + 1,agent_number)
= sim.(['time' num2str(time_index)]).(agent_name).('state');

```

```

        reward_matrix(time_index - min(time_index_vector) + 1,agent_number)
=   sim.(['time' num2str(time_index)]).(agent_name).('reward');
        state_value_matrix(time_index - min(time_index_vector)
+ 1,agent_number) = sim.(['time' num2str(time_index)]).(agent_name).
('state_value');
        action_value_matrix(time_index - min(time_index_vector)
+ 1,agent_number) = sim.(['time' num2str(time_index)]).(agent_name).
('action_value');
        cumulative_reward_matrix(time_index - min(time_index_vector) +
1,agent_number) = sum(reward_matrix(1:time_index - min(time_index_vector) +
1,agent_number));

    end

end

result = [time_index_vector' , result_matrix]

```

```

result = 31x101
    100     0     0     0     0     0     0     0     0     0     0     0     0 ...
    101     0     0     0     0     0     0     0     0     0     0     0    19     0
    102     0     0     0     0     0     0     0     0     0     7     0    20     0
    103     0     0     0     0     0     0     0     0     0     6     0    46     0
    104     0     0     0     0     0     0     0     0     5    28     0    47     0
    105     0     0     0     0     0     0     0     0     4    27     0     0     0
    106     0     0     0     0     0     0     0     0    25    26     0     0     0
    107     0    47     0     0     0     0     0     0    23    25     0     0     0
    108     0    48     0     0     0     0     0     0    22    48     0     0     0
    109    25     3     0     0     0     0     0     0    21    47     0     0     0
      ⋮

```

```

reward = [time_index_vector', reward_matrix]

```

```

reward = 31x101
    100     0     0     0     0     0     0     0     0     0     0     0     0 ...
    101     0     0     0     0     0     0     0     0     0     0     0    -1     0
    102     0     0     0     0     0     0     0     0     0    -1     0   -15     0
    103     0     0     0     0     0     0     0     0     0   -15     0    75     0
    104     0     0     0     0     0     0     0     0    -1    -1     0     0     0
    105     0     0     0     0     0     0     0     0   -15    -1     0     0     0
    106     0     0     0     0     0     0     0     0   -15    -1     0     0     0
    107     0    -1     0     0     0     0     0     0    -1    -1     0     0     0
    108     0   -15     0     0     0     0     0     0    -1    75     0     0     0
    109    -5    -1     0     0     0     0     0     0    -5     0     0     0     0
      ⋮

```

```

cumulative_reward = [time_index_vector', cumulative_reward_matrix]

```

```

cumulative_reward = 31x101
    100     0     0     0     0     0     0     0     0     0     0     0     0 ...
    101     0     0     0     0     0     0     0     0     0     0     0    -1     0
    102     0     0     0     0     0     0     0     0     0    -1     0   -16     0
    103     0     0     0     0     0     0     0     0     0   -16     0    59     0
    104     0     0     0     0     0     0     0     0    -1   -17     0    59     0
    105     0     0     0     0     0     0     0     0   -16   -18     0     0     0
    106     0     0     0     0     0     0     0     0   -31   -19     0     0     0
    107     0    -1     0     0     0     0     0     0   -32   -20     0     0     0

```

```

108      0   -16      0      0      0      0      0   -33    55      0      0      0
109     -5   -17      0      0      0      0      0   -38    55      0      0      0
  ⋮

```

```
state_value = [time_index_vector', state_value_matrix]
```

```

state_value = 31x101
100.0000      0      0      0      0      0      0      0 ...
101.0000      0      0      0      0      0      0      0
102.0000      0      0      0      0      0      0      0
103.0000      0      0      0      0      0      0      0
104.0000      0      0      0      0      0      0      0
105.0000      0      0      0      0      0      0      0
106.0000      0      0      0      0      0      0      0
107.0000      0  -26.0000      0      0      0      0      0
108.0000      0  -17.5000      0      0      0      0      0
109.0000  53.0000    2.5000      0      0      0      0      0
  ⋮

```

```
action_value = [time_index_vector', action_value_matrix]
```

```

action_value = 31x101
100.0000      0      0      0      0      0      0      0 ...
101.0000      0      0      0      0      0      0      0
102.0000      0      0      0      0      0      0      0
103.0000      0      0      0      0      0      0      0
104.0000      0      0      0      0      0      0      0
105.0000      0      0      0      0      0      0      0
106.0000      0      0      0      0      0      0      0
107.0000      0  -26.0000      0      0      0      0      0
108.0000      0  -19.5000      0      0      0      0      0
109.0000  43.0000    2.5000      0      0      0      0      0
  ⋮

```

VI.1 Chack Congestion Factor in Result Matrix

```

congestion_factor_vector = zeros(length(result(:,1)),1);
active_data_packet= zeros(length(result(:,1)),1);
active_sats = zeros(length(result(:,1)),1);

for result_index = 1:length(result(:,1))
    states_vector = result(result_index,2:end);
    active_agent_vector = states_vector(states_vector ~= 0);
    unique_active_agent_vector = unique(active_agent_vector);
    active_sats(result_index) = length(unique_active_agent_vector);
    active_data_packet(result_index) = length(active_agent_vector);
    congestion_factor_vector(result_index) = length(active_agent_vector) -
length(unique_active_agent_vector);
end

congestion_factor_vector'
```

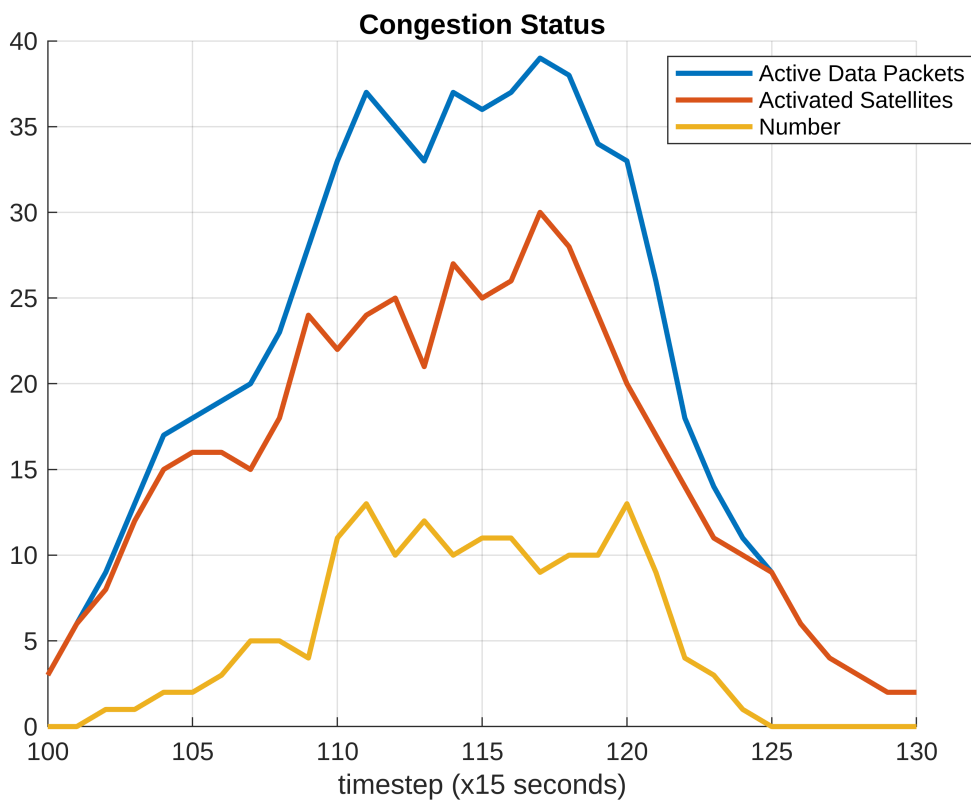
```
ans = 1x31
```

0 0 1 1 2 2 3 5 5 4 11 13 10...

```
congestion_factor_sum = sum(congestion_factor_vector)
```

```
congestion_factor_sum = 160
```

```
figure;  
hold on  
plot(time_index_vector', active_data_packet,'LineWidth',2)  
plot(time_index_vector', active_sats,'LineWidth',2)  
plot(time_index_vector', congestion_factor_vector,'LineWidth',2)  
grid on  
title('Congestion Status')  
xlabel('timestep (x15 seconds)')  
legend('Active Data Packets','Activated Satellites','Number')
```



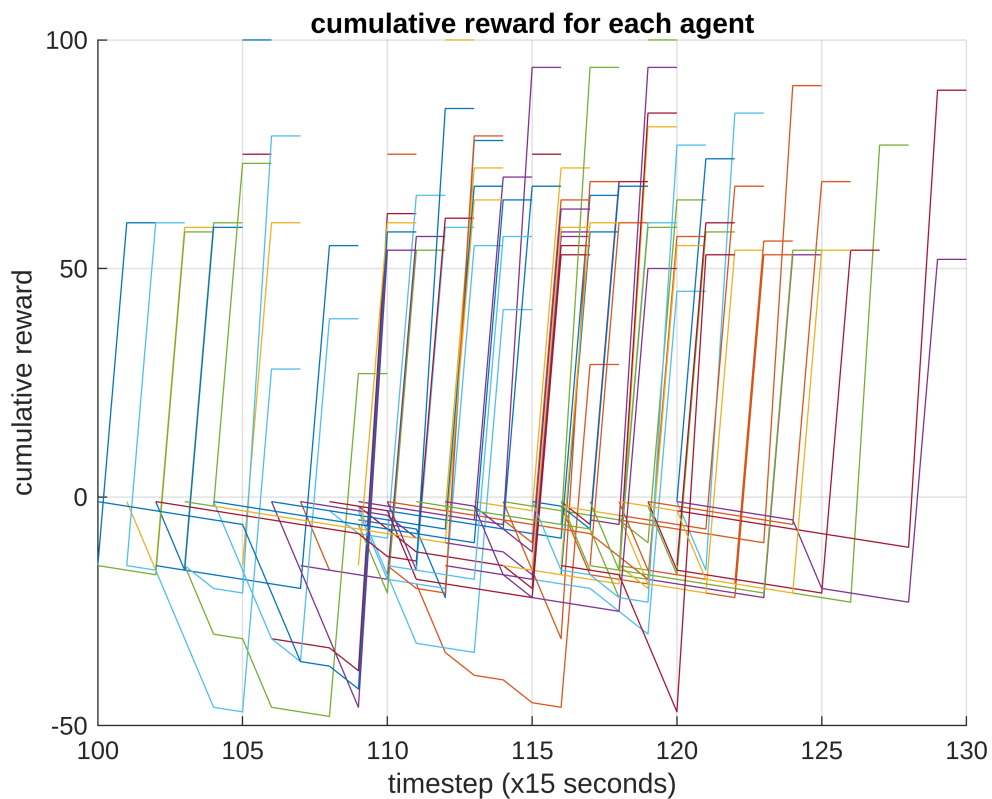
VII. Result Graph

```
number_of_agents = length(agents_input(:,1));  
  
final_cumulative_reward_vector = zeros(number_of_agents,1);  
  
figure;  
hold on
```

```

for agent_index = 1:number_of_agents
    cumulative_reward_each_agent = [time_index_vector',
    cumulative_reward_matrix(:,agent_index)];
    cumulative_reward_each_agent =
    cumulative_reward_each_agent(cumulative_reward_each_agent(:,2) ~= 0, :);
    plot(cumulative_reward_each_agent(:,1),cumulative_reward_each_agent(:,2))
end
hold off
grid on
title('cumulative reward for each agent')
xlabel('timestep (x15 seconds)')
ylabel('cumulative reward')

```



```

for agent_index = 1:number_of_agents
    each_agent_reward_vector = cumulative_reward_matrix(:,agent_index);
    each_agent_reward= each_agent_reward_vector(each_agent_reward_vector ~=
0);
    if isempty(each_agent_reward) == true
        continue;
    end
    final_cumulative_reward_vector(agent_index) = each_agent_reward(end);
end

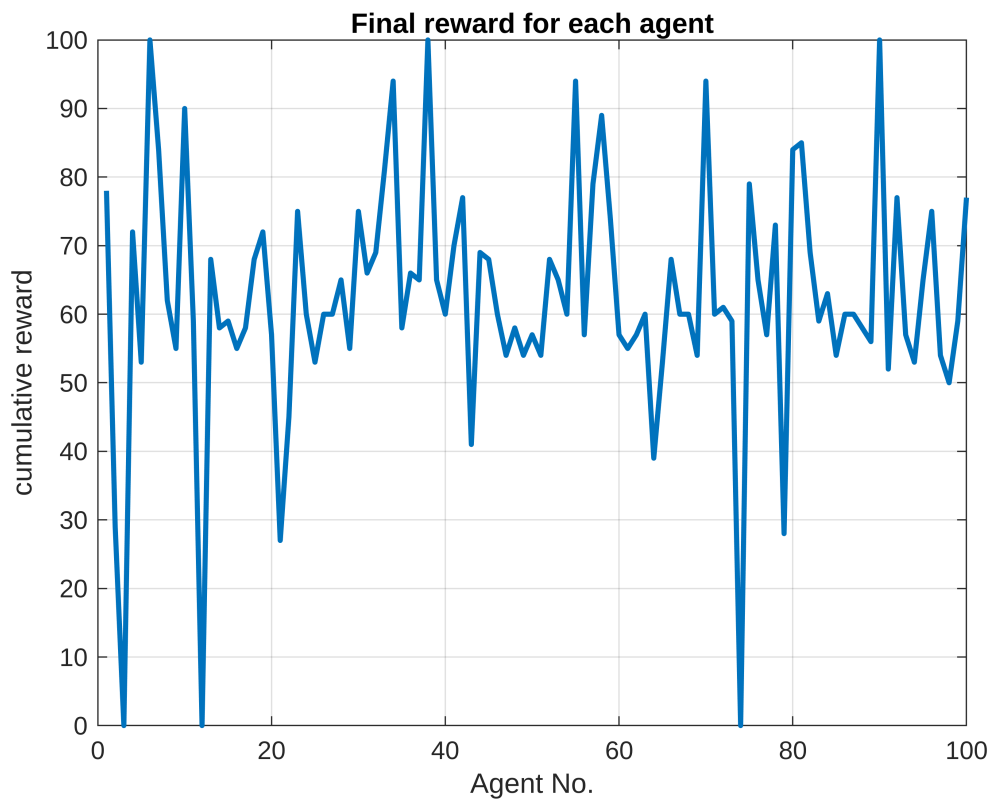
figure;
plot((1:number_of_agents)',final_cumulative_reward_vector,"LineWidth",2)
grid on

```

```

title('Final reward for each agent')
xlabel('Agent No.')
ylabel('cumulative reward')

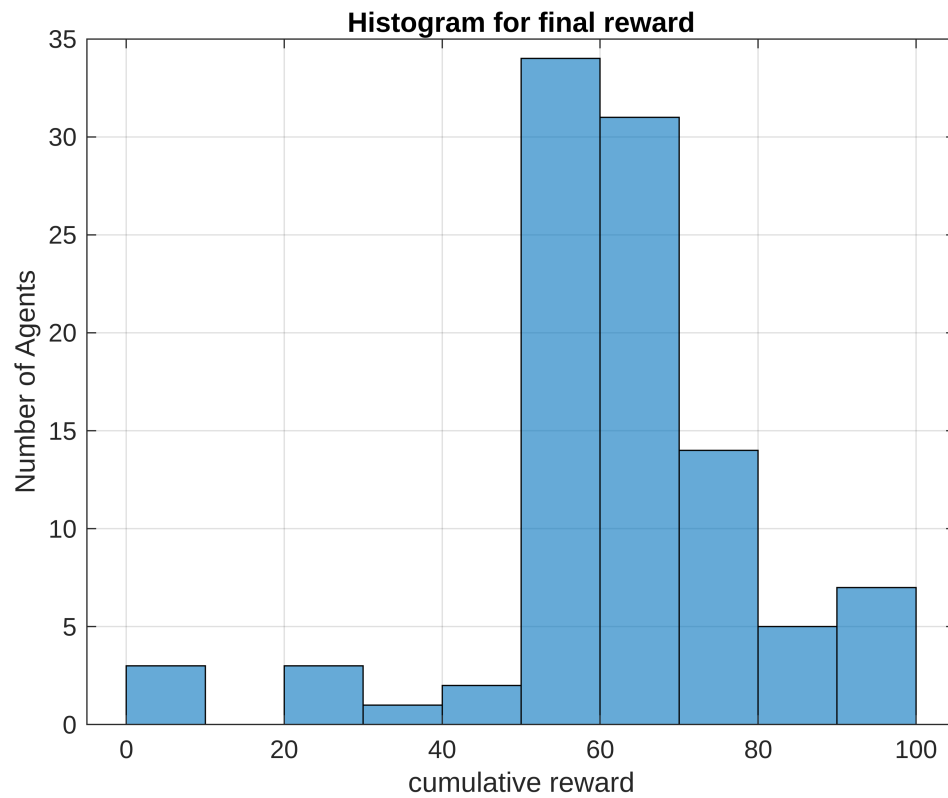
```



```

figure;
histogram(final_cumulative_reward_vector)
grid on
title('Histogram for final reward')
xlabel('cumulative reward')
ylabel('Number of Agents')

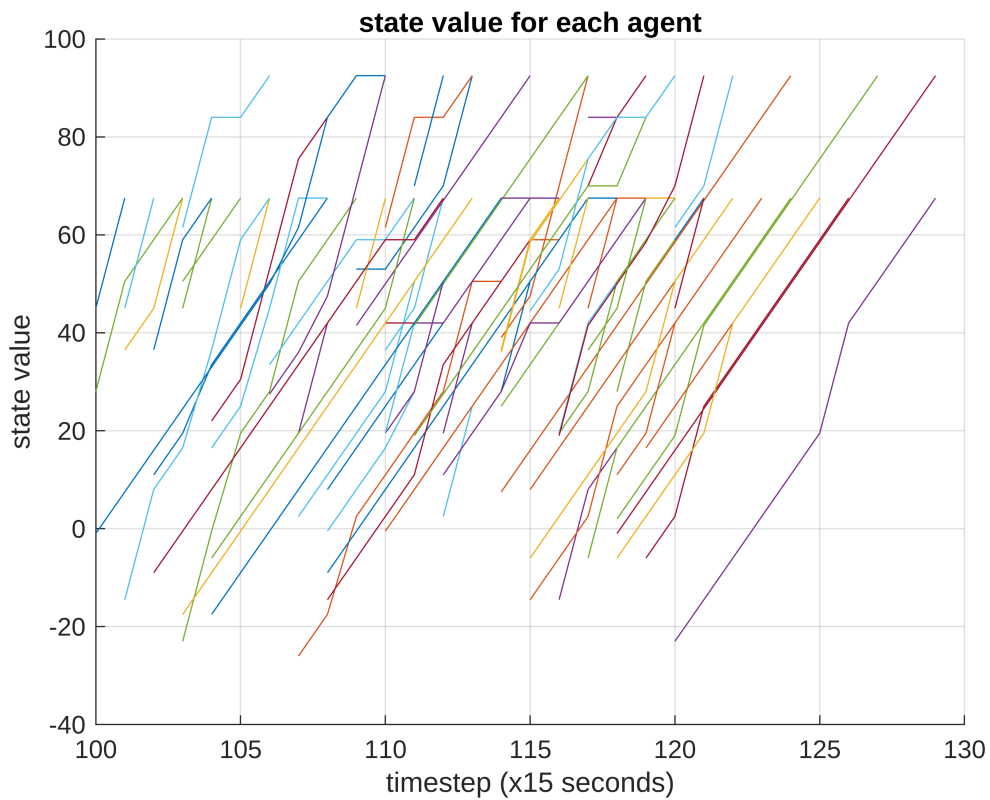
```

```
figure;
hold on
for agent_index = 1:number_of_agents

    state_value_each_agent = [time_index_vector',
state_value_matrix(:,agent_index)];
    state_value_each_agent =
state_value_each_agent(state_value_each_agent(:,2) ~= 0, :);

    plot(state_value_each_agent(:,1),state_value_each_agent(:,2))
end
hold off
grid on
title('state value for each agent')
xlabel('timestep (x15 seconds)')
ylabel('state value')
```



```
figure;
hold on
for agent_index = 1:number_of_agents

    action_value_each_agent = [time_index_vector',
    action_value_matrix(:,agent_index)];
    action_value_each_agent =
    action_value_each_agent(action_value_each_agent(:,2) ~= 0, :);
    plot(action_value_each_agent(:,1),action_value_each_agent(:,2))
end
hold off
grid on
title('action value for each agent')
xlabel('timestep (x15 seconds)')
ylabel('action value')
```



```
figure;
hold on
for agent_index = 1:number_of_agents

    state_value_each_agent = [time_index_vector',
state_value_matrix(:,agent_index)];
    state_value_each_agent =
state_value_each_agent(state_value_each_agent(:,2) ~= 0, :);

plot(state_value_each_agent(:,1),state_value_each_agent(:,2),'b','LineWidth',
2)
end

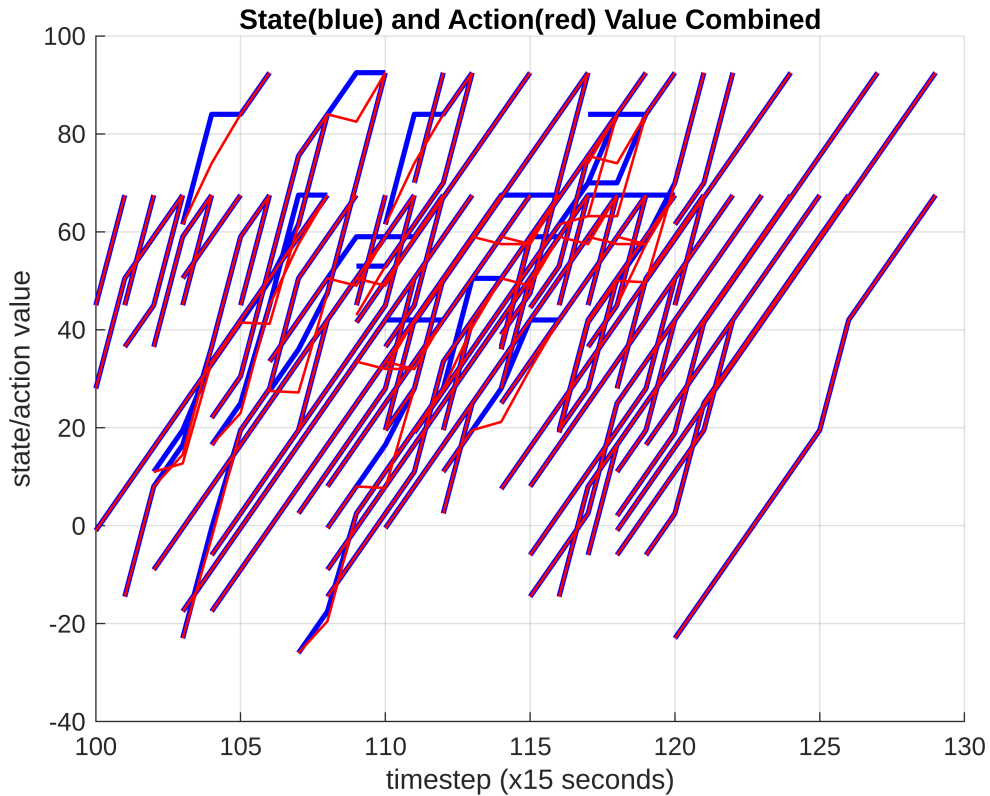
for agent_index = 1:number_of_agents

    action_value_each_agent = [time_index_vector',
action_value_matrix(:,agent_index)];
    action_value_each_agent =
action_value_each_agent(action_value_each_agent(:,2) ~= 0, :);
```

```

plot(action_value_each_agent(:,1),action_value_each_agent(:,2),'r','LineWidth',1)
end
hold off
grid on
title('State(blue) and Action(red) Value Combined')
xlabel('timestep (x15 seconds)')
ylabel('state/action value')

```



```

figure;
hold on
for agent_index = 1:number_of_agents
    result_sorted = [result(:,1), result(:,1+agent_index)];
    result_sorted_nonzero = result_sorted(result_sorted(:,2) ~= 0,:);
    plot(result_sorted_nonzero(:,1),result_sorted_nonzero(:,2))
end
hold off
grid on
title('Network Trajectory By Each Agent')
xlabel('timestep (x15 seconds)')
ylabel('Satellite No.')

```

