



Universität St.Gallen

Task-level Collaborative Ad-hoc AGVs for Efficient Warehouse Logistics

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From insight to impact

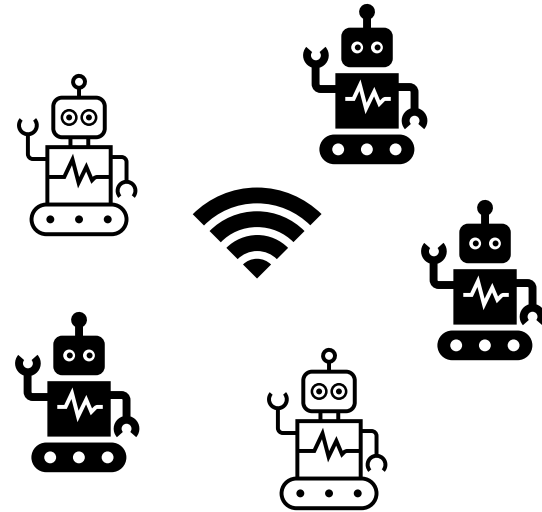


Achieving Collaboration in AGV systems

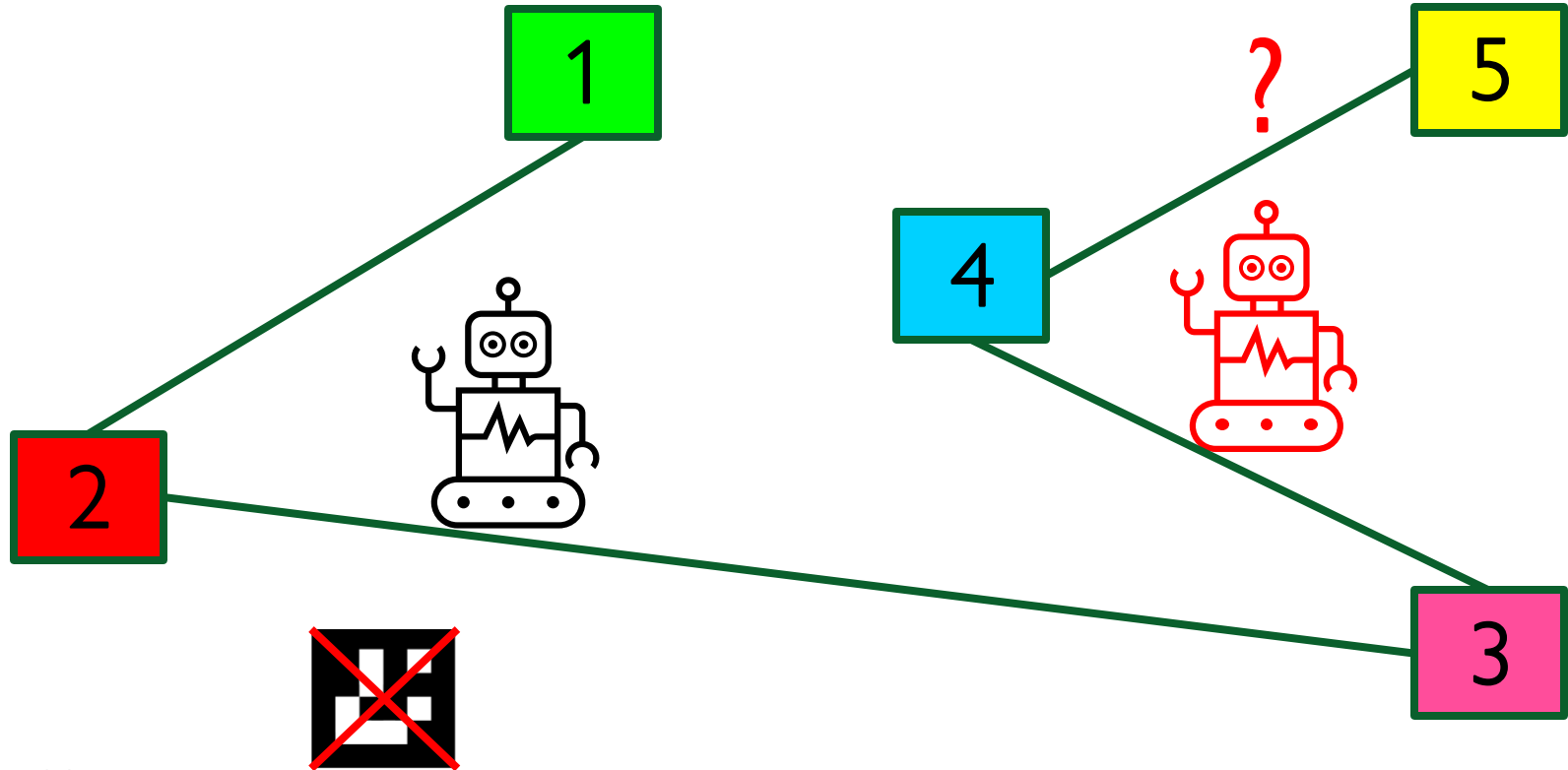
Automated Guided Vehicles



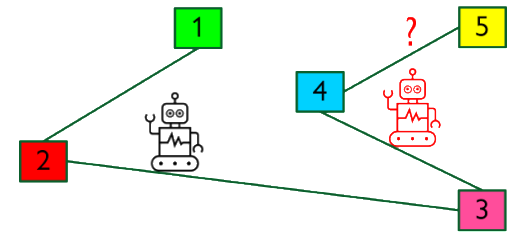
Autonomous task coordination



Baseline Setup

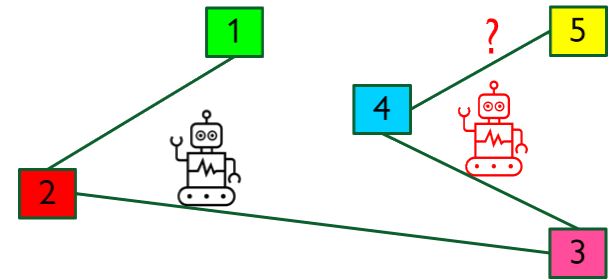


Required Actions during Task Execution



Conventional Approach		Collaborative Approach	
Robot A	Robot B1	Robot B2	
Drive	Drive	Drive	
Pick up	Pick up	Idle	
Transport	Transport		
Drop off	Drop off		
		Pick up	
		Transport	
		Drop off	

Actual Operational Steps



# actions	Conventional Approach	Collaborative Approach	
	Robot A	Robot B1	Robot B2
Driving	0	0	2
Pick up	1	1	1
Transport	4	2	2
Drop off	1	1	1
Idle	0	0	2
	6 steps	12 steps (8 steps actual)	

Preliminary Results

	Conventional	Collaborative
Single Task Execution	100%	75% slower
Consecutive Task Execution	200%	4.5% slower
Consecutive Task Execution	300%	2% slower

Discussion

- Pick-up and drop-off times can highly vary due to environment and mechanic's of the individual robot
- Warehouse layout, including floorplans and travel distances, have a high influence on the cooperation of robots.
 - Relatively longer paths may benefit from task-level cooperation as it can reduce idle times
 - Relatively shorter paths may degrade performance due to the latency induced by robotic arms handling parcels

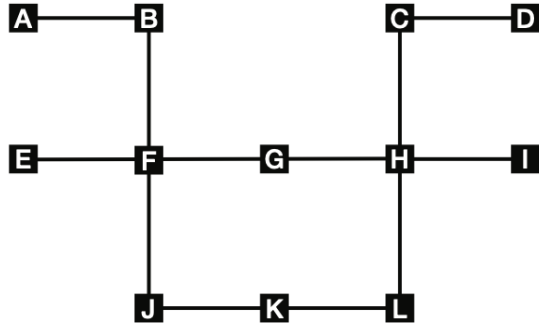


Further problems arise in more complex environments as a node or edge is being blocked

Further Ideas

Extend Environment

- More nodes and edges
- Up to eight robots



Simulation

- Handle more edge cases
- Easily scalable
- Likely more time-efficient





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Join our robots at our booth
for a *competitive* race

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Image source: ChatGPT

Q & A

Questions?



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