NavSim

2.8.2-dev

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Contents

CHAPTER 1

Introduction

A navigation simulator API built on top of Python, Stable Baselines 3, Pytorch.

Can use many simulator backends, for now uses the Aurora Simulator, that is a Unity3D GameEngine based Berlin city environment.

1.1 Pre-requisites

Following should be pre-installed on the host machine:

1.1.1 For running inside the containers

- nvidia driver
- docker
- nvidia container toolkit

1.1.2 For directly running on the host

- Anaconda or Miniconda
- X-window system
- nvidia drivers

1.2 Versions

There are three components: navsim binary, navsim python api, navsim container You can use any version of each of them as long as first two digits match. These are latest releases of each of them:

- binary 2.8.1
- python api 2.8.1
- container 2.8.1

1.3 How to use the navsim env

Assuming your code is in a folder defined in environment variable `expdir`. In your code import `NavSimGymEnv` from the `navsim` package. Either use it to instantiate env objects or extend it by subclassing.

Follow the instructions in "how to run the navsim training" section below, replace `navsim` command with your own command, for example: `my-training`

1.4 How to run the navsim training

You can either run directly on a host machine or in a container. If you are running on a host directly, first follow the instructions to setup the host.

1. Download and extract the unity binary zip file, and
2. The following environment variables need to be set in both cases:

```
envdir=$(realpath "/data/work/unity-envs/Build2.8.1"); envbin="Berlin_Walk_V2.x86_64";␣
↪expdir=$(realpath "$HOME/exp");
repo="ghcr.io/armando-fandango"; cname="$(hostname)_navsim_1"
```

1. Now follow the container, or the host option below.

1.4.1 Option 1: Container

```
cd $expdir
docker run --rm --privileged -it --runtime=nvidia \
--name $cname \
-h $cname \
-e XAUTHORITY \
-e NVIDIA_VISIBLE_DEVICES=all -e NVIDIA_DRIVER_CAPABILITIES=all \
-e USER_ID=$(id -u) -e USER_HOME="$HOME" \
-v $HOME:$HOME \
-v /etc/group:/etc/group:ro \
-v /etc/passwd:/etc/passwd:ro \
-v /etc/shadow:/etc/shadow:ro \
-v $envdir:$envdir \
-v $expdir:$expdir \
-w $expdir \
$repo/navsim:2.8.1 DISPLAY=:0.0 <navsim command>
```

The Variable `DISPLAY=:0.0`

The display variable points to X Display server, and takes a value of `hostname:D.S`, where:

- `hostname` can be empty.
- `D` refers to the display index, which is 0 generally.
- `S` refers to the screen index, which is 0 generally but in a GPU based system, each GPU might be connected to a different screen. In our container, this number refers to the GPU on which the environment binary will run.

For the purpose of navsim container, use `DISPLAY=:0.0` and change the last zero to the index number if GPU where environment binary can run.

1.4.2 Option 2: Run on host directly - doesn't run headless.

To run on the host, activate the `navsim` virtual environment, only once, with following command: `conda activate navsim || source activate navsim`.

Now the navsim env should be activated. If not then go to host setup steps and troubleshoot.

Run the `navsim` command as described in its section below.

1.4.3 The `<navsim command>`

- `navsim --help` shows the options
- `navsim --env $envdir/$envbin` - executes and/or trains the model
- `navsim-benchmark $envdir/$envbin` - benchmarks the model
- `navsim-saturate-gpu $envdir/$envbin` - Saturates the GPU
- Replace the navsim command with your own command if you are just importing the NavSim env.

1.5 Setup the host to run directly

1.5.1 Assumptions

- Following are installed: X, nvidia drivers
- Miniconda or Anaconda is installed, and is in the path.

1.5.2 Steps

1. set the shell variable CONDA_DIR to the location of Miniconda or Anaconda install. For example on my laptop it is set as CONDA_DIR="/opt/conda".
2. `sudo chmod 777 $CONDA_DIR/envs`
3. Download following files:

- `ezai-conda.sh`
- `ezai-conda-req.txt`
- `ezai-pip-req.txt`

1. Run the following command:

```
source ezai-conda.sh && ezai_conda_create --venv "$CONDA_DIR/envs/navsim"`
```

1.6 TODO: Clean up the following section

For tmux hotkeys press ctrl+b then following key

- Start tmux session: tmux new -s
- Open another tmux shell: ctrl + b, % (vertical pane) Or ctrl + b, " (horizontal pane)
- Move between panes: ctrl + <left, right, up, down>
- Detach from tmux session: ctrl + b, d (detach from tmux session)
- Attach to existing tmux session: tmux attach -t
- Exit Session: Type exit into all open shells within session

1.7 TODO: To run the singularity container

Note: Do it on a partition that has at least 10GB space as the next step will create navsim_0.0.1.sif file of ~10GB.

singularity pull docker://$repo/navsim$:ver singularity shell –nv -B not needed if path to binary is inside $HOMEfolder - B < absolutepathofcurrentfolder > notneededifpathtocurrentfolderisinside$HOME folder navsim_$ver.sif

For IST Devs: From local docker repo for development purposes:

SINGULARITY_NOHTTPS=true singularity pull docker://$repo/navsim$:ver

CHAPTER 2

Navsim Environment Tutorial

NavSimGymEnv Class is a wrapper to Unity2Gym that inherits from the Gym interface The configuration provided is as follows:

2.1 Config Parameters

```
env_config = ObjDict({
    "log_folder": "unity.log",
    "seed": 123,
    "timeout": 600,
    "worker_id": 0,
    "base_port": 5005,
    "observation_mode": 2,
    "segmentation_mode": 1,
    "task": 0,
    "goal": 0,
    "goal_distance":50
    "max_steps": 10,
    "reward_for_goal": 50,
    "reward_for_ep": 0.005,
    "reward_for_other": -0.1,
    "reward_for_falling_off_map": -50,
    "reward_for_step": -0.0001,
    "agent_car_physics": 0,
    "episode_max_steps": 10,
    "env_path":args["env_path"]
})
```

2.1.1 Observation Mode

0 - Vector - Returns [Agent Position (3-x,y,z) ,Agent Velocity (3-x,y,z), Agent Rotation(4-x,y,z,w), Goal Position (3-x,y,z,w)]1 - Visual- Returns [[Raw Agent Camera](84,84,3), [Depth Agent Camera](84,84,1), [Segmentation Agent Camera](84,84,3)]2 - VectorVisual - Returns [[Raw Agent Camera](84,84,3), [Depth Agent Camera](84,84,1), [Segmentation Agent Camera](84,84,3), [Agent Position (3-x,y,z) ,Agent Velocity (3-x,y,z), Agent Rotation (4-x,y,z,w), Goal Position (3-x,y,z,w)]]

2.1.2 Segmentation Mode

0 - Object Seg: Each gameobject in the scene is a unique color1 - Tag Seg: Gameobject colors are based on the tag assigned such that all objects with the same tag share a color. (E.g. Car, Tree, Buildings)2 - Layer Seg: Similar to tag segmentation but with the physics layers. Current layers (Default, Trees, Tree Colliders, Agent Vehicle, Autonomous Vehicle, Parked Vehicle)

2.1.3 Task

0 - PointNav - Agent is randomly placed along with a randomly place goal position. The agent must navigate to the goal position.1 - SimpleObjectNav1 - The Agent is place at a specified starting location (manually identified traffic intersection). Goal is a sedan 40m forward in a straight line of the agent. The goal is to reach that sedan.2 - ObjectNav - The Agent is randomly place and goal object is defined by the goal parameter. The agent must reach one instance of the goal object. E.g. The goal object is a sedan and there any multiple sedans in the scene. Reaching any of the sedans results in a success.

2.1.4 Goal : Only relevant for SimpleObjectNav and ObjectNav

0 - Tocus1 - sedan12 - Car13 - Car24 - City Bus5 - Sporty_HatchbackElse - SEDAN

2.1.5 Rewards

reward_for_goal : For pointnav goal is the target position to complete the task.reward_for_ep : Exploration points are randomly placed in the environment to reward exploration.reward_for_other : Other collision are anythin that is not a goal point or exploration point, this includes other cars, building, trees, etc.reward_for_falling_off_map : The map is a tiled XXkm area. If the agent goes outside of this area falls XXm below the environment area this reward is activated. This will also result in a reset.reward_for_step : This reward will be given at every step in addition to any other reward recieved at the same step.

2.1.6 Agent Car Physics

0 - Simple : Collisions and gravity only - An agent that moves by a specific distance and direction scaled by the provided action. This agent only experiences collision and gravity forces1 - Intermediate 1 : Addition of wheel torque2 - Intermediate 2 : Addition of suspension, downforce, and sideslip10 - Complex : Addition of traction control and varying surface friction

2.2 Action Space:

[Throttle, Steering, Brake]`Throttle` : -1.0 to 1.0 : Moves the agent forward`Steering` : -1.0 to 1.0 : Turns the steering column of the vehicle left or right`Brake` : 0.0 to 1.0 : Reduces the agents current velocity

2.3 Observation Space:

2.3.1 The vector observation space

```
Agent_Position.x, Agent_Position.y, Agent_Position.z,
Agent_Velocity.x, Agent_Velocity.y, Agent_Velocity.z,
Agent_Rotation.x, Agent_Rotation.y, Agent_Rotation.z, Agent_Rotation.w,
Goal_Position.x, Goal_Position.y, Goal_Position.z
```

2.3.2 The visual observation space

[[Raw Agent Camera],[Depth Agent Camera],[Segmentation Agent Camera], [Agent Position, Agent Velocity, Agent Rotation, Goal Position]]

2.4 Queries from the Env

2.4.1 Map

Used to request and receive a binary navigable map. The binary map indicates navigable and obstacle areas.

Map requests to Unity are sent using:

```
NavSimGymEnv.start_navigable_map(resolution_x, resolution_y, cell_occupancy_threshold)
```

The map is then retrieved with:

```
NavSimGymEnv.get_navigable_map()
```

2.4.2 Postion Scan - Not Available

Given a position and this returns the attribution data of the first object found at the given position. Objects are searched for within a 1 meter radius of the given position. If the position is not loaded in the environment then None will be returned.

2.4.3 Shortest Path from Starting Location to Goal

`ShortestPath` : Returns the shortest path value from the agent's start location to the goal position from the navigable area.

```
NavSimGymEnv.get_shortest_path_length()
```

CHAPTER 3

Contributing to NavSim API

3.1 General dev info:

- Use only google style to document your code: https://sphinxcontrib-napoleon.readthedocs.io/en/latest/example_google.html#example-google

3.2 How to setup dev laptop to code for navsim API

- clone the ai_coop_py repo

```
git clone <blah blah>
```

- Install miniconda and the env

```
NAVSIM_ROOT=~/projects/ai_coop_py
cd $NAVSIM_ROOT/navsim_env
sudo mkdir /opt/conda
sudo chown $(id -u) /opt/conda
source ezai-conda.sh && install-miniconda
exit

NAVSIM_ROOT=~/projects/ai_coop_py
cd $NAVSIM_ROOT/navsim_env
rm -rf /opt/conda/envs/navsim; source ezai-conda.sh; ezai_conda_create --venv "/opt/
↪conda/envs/navsim"
conda activate navsim
cd $NAVSIM_ROOT
pip install -e .
```

3.3 Testing from local repo

For IST Devs: From local docker repo for development purposes:

```
repo="localhost:5000"
```

CHAPTER 4

NavSim API

4.1 NavSim Environment

class navsim.**NavSimGymEnv**(*env_config*)

Bases: gym_unity.envs.UnityToGymWrapper

NavSimGymEnv Class is a wrapper to Unity2Gym that inherits from the Gym interface

Read the **NavSim Environment Tutorial** on how to use this class.

close() → None

Override _close in your subclass to perform any necessary cleanup. Environments will automatically close() themselves when garbage collected or when the program exits.

get_navigable_map() → numpy.ndarray

Get the Navigable Areas map

Parameters

- **resolution_x** – The size of the x axis of the resulting grid, default = 200
- **resolution_y** – The size of the y axis of the resulting grid, default = 200
- **cell_occupancy_threshold** – If at least this much % of the cell is occupied, then it will be marked as non-navigable, default = 50%

Returns A numpy array which has 0 for non-navigable and 1 for navigable cells

Note: This method only works if you have called `reset()` or `step()` on the environment at least once.

Note: Largest resolution that was found to be working was 2000 x 2000

info()

Prints the information about the environment

info_steps(*save_visuals=False*)
Prints the initial state, action sample, first step state

property metadata
dict() -> new empty dictionary dict(mapping) -> new dictionary initialized from a mapping object's

(key, value) pairs

dict(iterable) -> new dictionary initialized as if via: d = {} for k, v in iterable:

d[k] = v

dict(kwargs) -> new dictionary initialized with the name=value pairs** in the keyword argument list. For example: dict(one=1, two=2)

property observation_space_shapes: list
Returns the dimensions of the observation space

property observation_space_types: list
Returns the dimensions of the observation space

static register_with_gym()
Registers the environment with gym registry with the name navsim

static register_with_ray()
Registers the environment with ray registry with the name navsim

render(*mode=''*) → None
Not implemented yet

Parameters mode –

Returns:

reset() → Union[List[numpy.ndarray], numpy.ndarray]
Resets the state of the environment and returns an initial observation. Returns: observation (object/list): the initial observation of the space.

property reward_range: Tuple[float, float]
Built-in immutable sequence.

If no argument is given, the constructor returns an empty tuple. If iterable is specified the tuple is initialized from iterable's items.

If the argument is a tuple, the return value is the same object.

seed(*seed: Optional[Any] = None*) → None
Sets the seed for this env's random number generator(s). Currently not implemented.

property sim
Returns itself

Added for compatibility with habitat API.

Returns: link to self

start_navigable_map(*resolution_x=200*, *resolution_y=200*, *cell_occupancy_threshold=0.5*)
Get the Navigable Areas map

Parameters

- **resolution_x** – The size of the x axis of the resulting grid, default = 200
- **resolution_y** – The size of the y axis of the resulting grid, default = 200

- **cell_occupancy_threshold** – If at least this much % of the cell is occupied, then it will be marked as non-navigable, default = 50%

Returns A numpy array which has 0 for non-navigable and 1 for navigable cells

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Note: This method only works if you have called `reset()` or `step()` on the environment at least once.

Note: Largest resolution that was found to be working was 2000 x 2000

---

step(*action: List[Any]*) → Tuple[numpy.ndarray, float, bool, Dict]
Run one timestep of the environment's dynamics. When end of episode is reached, you are responsible for calling *reset()* to reset this environment's state. Accepts an action and returns a tuple (observation, reward, done, info). :param action: an action provided by the environment :type action: object/list

Returns agent's observation of the current environment reward (float/list) : amount of reward returned after previous action done (boolean/list): whether the episode has ended. info (dict): contains auxiliary diagnostic information.

Return type observation (object/list)

property unwrapped
Completely unwrap this env.

Returns The base non-wrapped gym.Env instance

Return type gym.Env

4.2 NavSim Utilities

class navsim.util.**ObjDict**
Bases: `dict`

A data structure that inherits from dict and adds object style member access

clear() → None. Remove all items from D.

copy() → a shallow copy of D

deepcopy()
Make a deep copy of itself

Returns ObjDict object

fromkeys(*value=None*, */*)
Create a new dictionary with keys from iterable and values set to value.

get(*key*, *default=None*, */*)
Return the value for key if key is in the dictionary, else default.

items() → a set-like object providing a view on D's items

keys() → a set-like object providing a view on D's keys

static load_from_file(*filename*)
load objdict from a file

Parameters **filename** – path or name of the file

Returns ObjDict object

static load_from_json_file(*filename*)
load objdict from a file

Parameters **filename** – path or name of the file

Returns ObjDict object

static load_from_yaml_file(*filename*)
load objdict from a file

Parameters **filename** – path or name of the file

Returns ObjDict object

pop(*k*[, *d*]) → v, remove specified key and return the corresponding value.
If key is not found, d is returned if given, otherwise KeyError is raised

popitem()
Remove and return a (key, value) pair as a 2-tuple.

Pairs are returned in LIFO (last-in, first-out) order. Raises KeyError if the dict is empty.

save_to_json_file(*filename*, *sort_keys=False*, *indent=2*)
Save to json file

Parameters

- **filename** – path or name of the file
- **sort_keys** – whether to sort the keys
- **indent** – indentation of the spaces

Returns:

save_to_yaml_file(*filename*)
Save to yaml file

Parameters **filename** – path or name of the file

Returns:

setdefault(*key*, *default=None*, */*)
Insert key with a value of default if key is not in the dictionary.

Return the value for key if key is in the dictionary, else default.

to_dict()
convert to dict

Returns dict object

to_json(*sort_keys=False*, *indent=2*)
convert to json

Parameters

- **sort_keys** – Sort the keys of dict or not, default False
- **indent** – indentation for JSON struct, default 2 spaces

Returns json string

to_yaml()
convery to yaml representation

Returns yaml string

update(*[E]*, ***F*) → None. Update D from dict/iterable E and F.
If E is present and has a .keys() method, then does: for k in E: D[k] = E[k] If E is present and lacks a .keys() method, then does: for k, v in E: D[k] = v In either case, this is followed by: for k in F: D[k] = F[k]

values() → an object providing a view on D's values

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