

# A Penny for Your Thoughts: The Value of Communication in Ad Hoc Teamwork

Reuth Mirsky, **William Macke**, Andy Wang,  
Harel Yedidsion, Peter Stone

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# Ad Hoc Teamwork

“To create an autonomous agent that is able to efficiently and robustly **collaborate** with **previously unknown** teammates on tasks to which they are all individually capable of contributing as team members”.

Stone, P., Kaminka, G. A., Kraus, S., & Rosenschein, J. S. (2010, July). **Ad Hoc Autonomous Agent Teams: Collaboration without Pre-Coordination**. In AAAI Conference on Artificial Intelligence (p. 6).



# Communication in Ad Hoc Teamwork (CAT)

Previously unknown teammates  $\neq$  solo player

**Use** existing communication channels

**Learn** new communication channels

**Teach** other teachable agents



Ackerman, E. "**Moxi Prototype from Diligent Robotics Starts Helping Out in Hospitals.**" *IEEE Spectrum*.

<https://spectrum.ieee.org/automaton/robotics/industrial-robots/moxi-prototype-from-diligent-robotics-starts-helping-out-in-hospitals> (2018).

# SOMALI CAT

**S**equential

**O**ne-shot

**M**ulti-

**A**gent

**L**imited

**I**nquiry

**C**ommunication

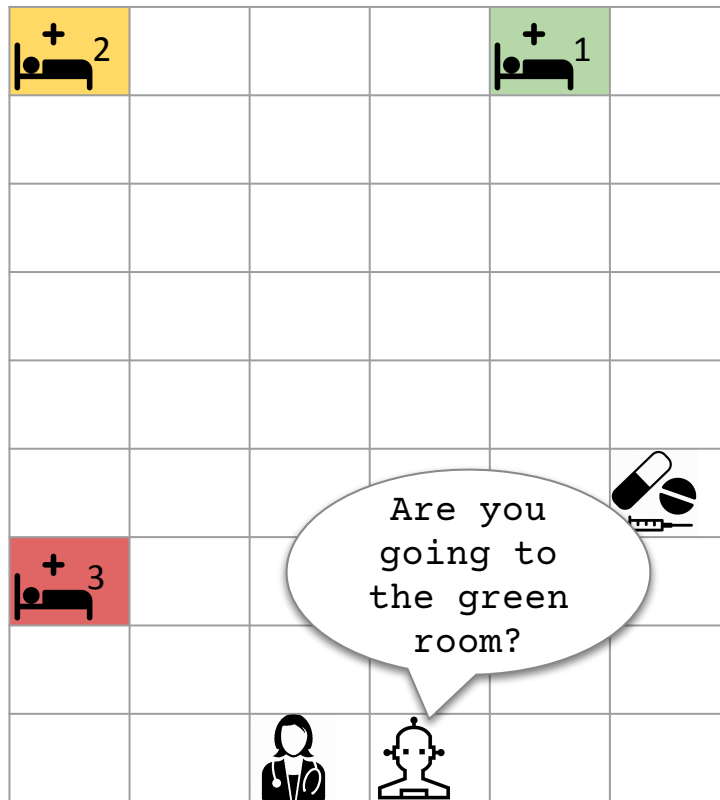
in

**A**d hoc

**T**eamwork



Are you going to the green room?



# When to Communicate

Zone of Information ( $Z_I$ )

Ad hoc agent may have

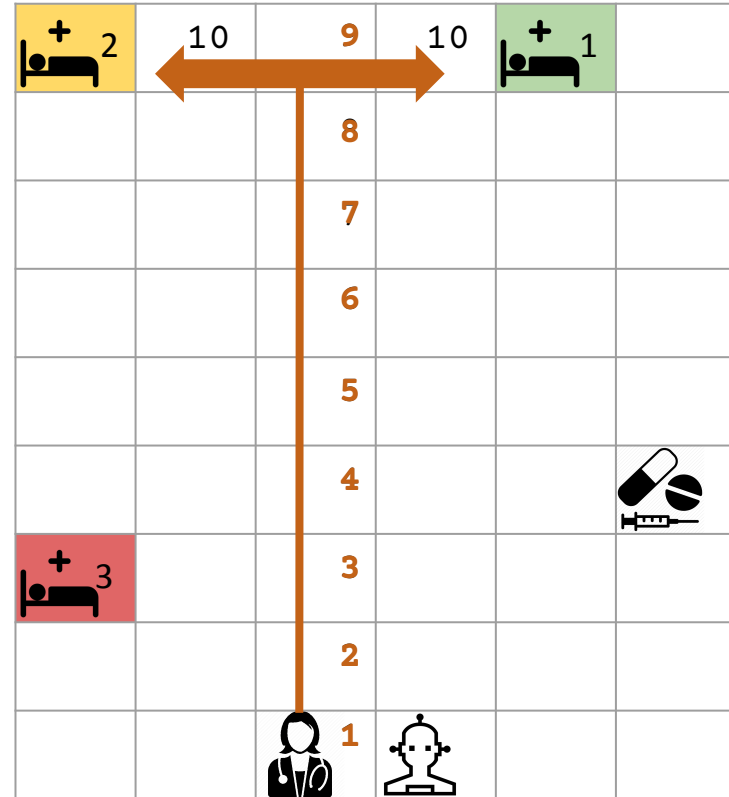
**Uncertainty** about the physician's goal

worst cases distinctiveness ( $wcd$ )<sup>1</sup>

$$Z_I = \{t \mid t \leq wcd_T(i,j)\}$$

$$Z_I(1,2) = 1-9$$

1. Keren, S., Gal, A., and Karpas, E. (2014). **Goal recognition design**. In ICAPS.



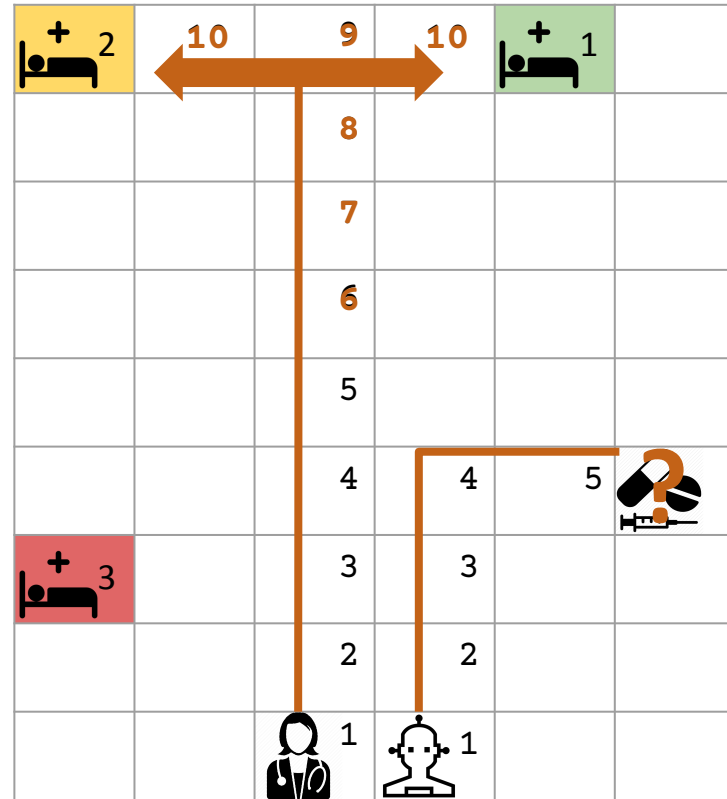
# When to Communicate

Zone of Plan Branching ( $Z_B$ )

Ad hoc agent must  
**commit** to goal

$$Z_B = \{t \mid t \geq wcd_A(i,j)\}$$

$$Z_B(1,2) = 6-10$$



# When to Communicate

Query when:

Ad hoc agent both is

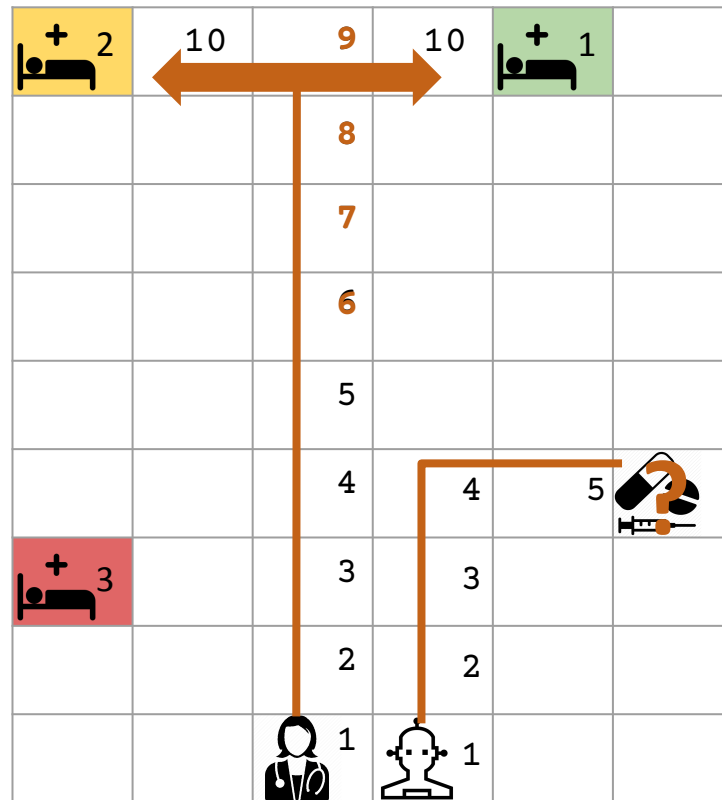
**uncertain** and must  
**commit**

Zone of Querying

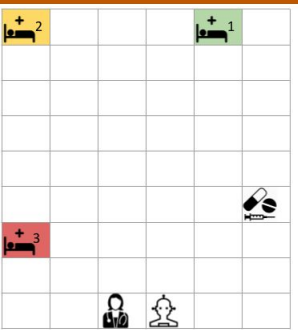
$$Z_Q = Z_I \cap Z_B$$

$$Z_Q = \{6, 7, 8, 9\}$$

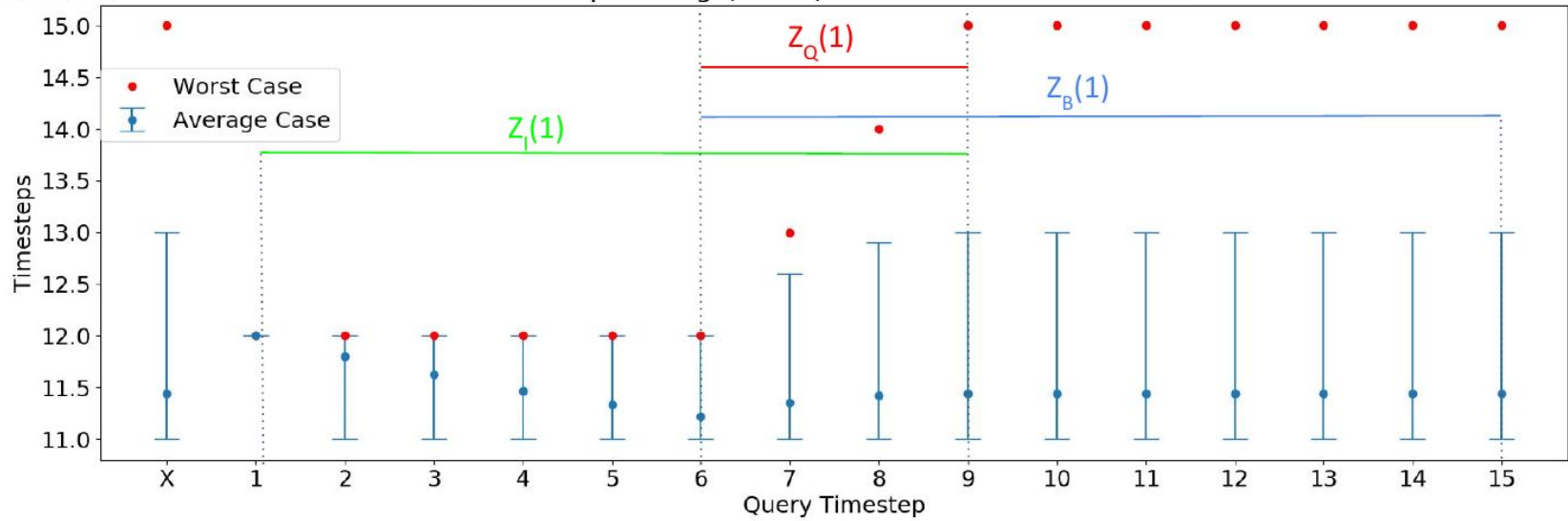
Critical Querying Point(CQP) = 6



# Methodical evaluation

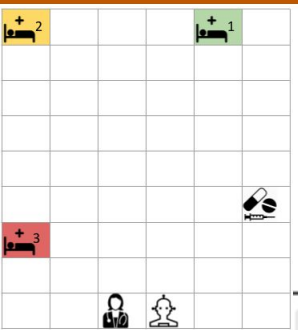


Timestep Average, Error, and Worst Case: Station 1

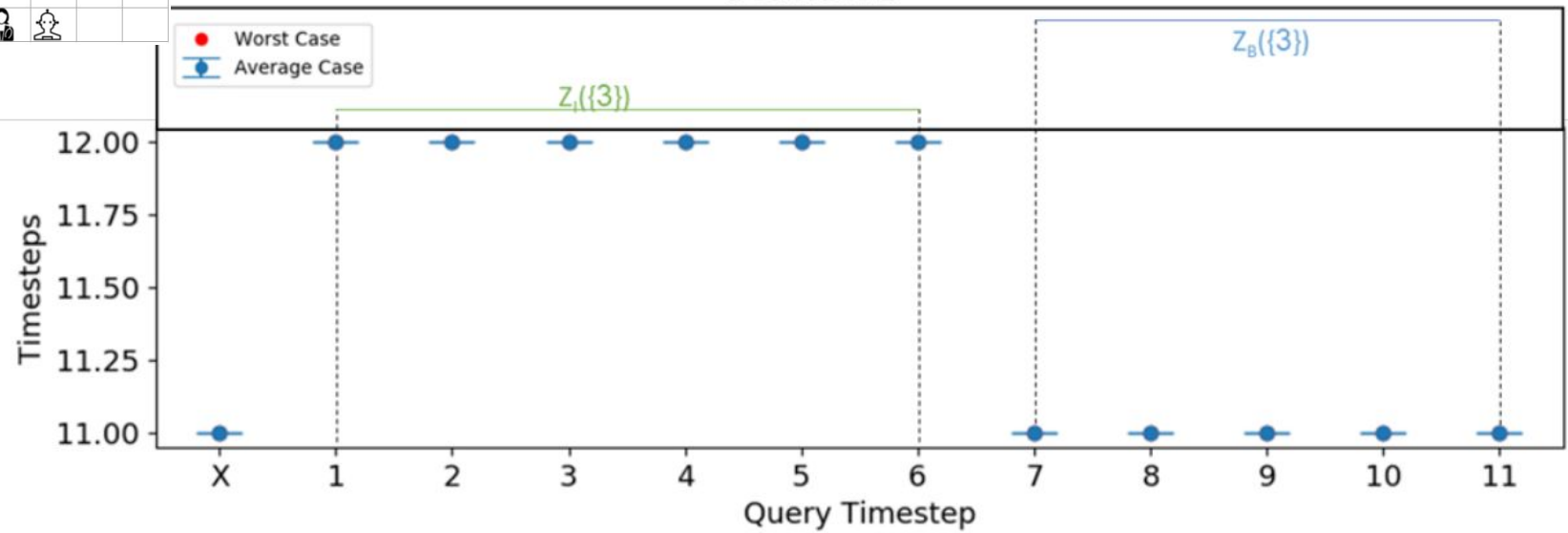




# Methodical Evaluation



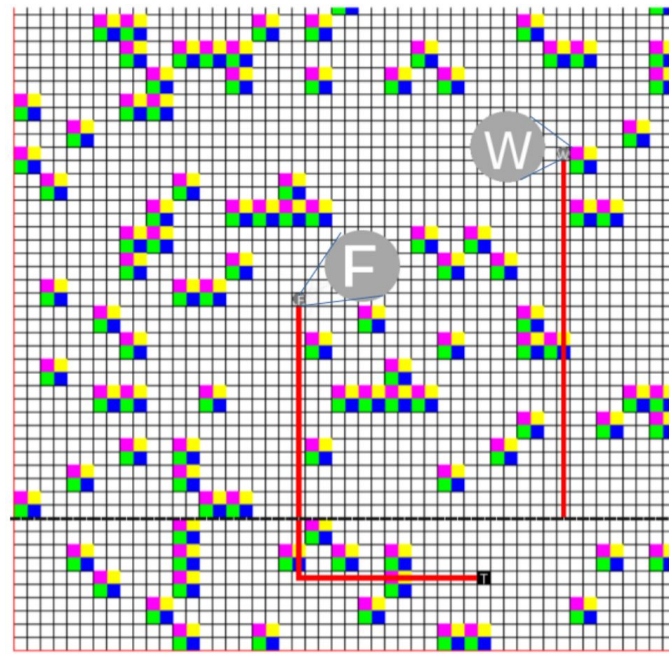
Station 3



# Experimental Setup

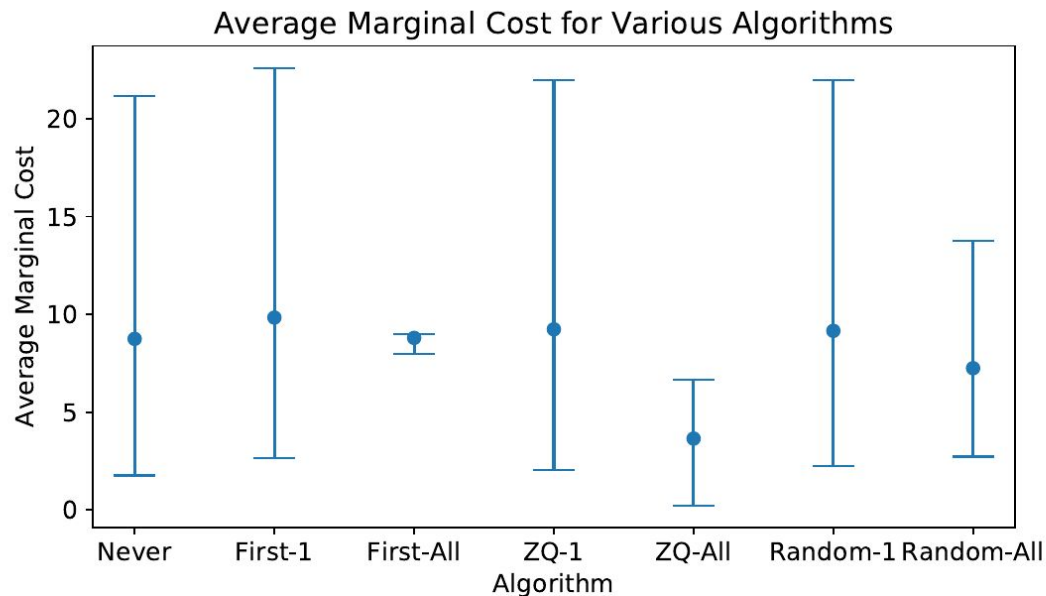
- Never
  - Only use Bayesian inference
- First
  - Query at beginning of simulation
- $Z_Q$ 
  - Query at beginning of Zone of Querying
- Random
  - Query randomly during simulation
- All vs One
  - Query until certain vs once

50x50 grid with 100 domain instances



# Results

- **Never**
  - Only use Bayesian inference
- **First**
  - Query at beginning of simulation
- **$Z_Q$** 
  - **Query at beginning of  $Z_Q$**
- **Random**
  - Query randomly during simulation
- **All vs One**
  - Query until certain vs once



# Summary

- We present **Communication in ad hoc teamwork (CAT)** as a novel paradigm for representing various real world tasks
- We introduce **The Tool Fetching Domain** as a new problem setting for representing CAT tasks
- We demonstrate that **Value of communication** is significantly dependent on timing

# Would you like to hear more?



<https://www.cs.utexas.edu/~pstone/Papers/bib2html/b2hd-IJCAI2020-Mirsky.html>



*Expected Value of Communication for Planning in Ad Hoc Teamwork in AAI'21*



Reuth Mirsky, [reuth@cs.utexas.edu](mailto:reuth@cs.utexas.edu)  
 William Macke, [wmacke@cs.utexas.edu](mailto:wmacke@cs.utexas.edu)  
 Andy Wang, [andywang6666@yahoo.com](mailto:andywang6666@yahoo.com)  
 Harel Yedidsion, [harel@cs.utexas.edu](mailto:harel@cs.utexas.edu)  
 Peter Stone, [pstone@cs.utexas.edu](mailto:pstone@cs.utexas.edu)

