

# **CS344M**

# **Autonomous Multiagent Systems**

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The University of Texas at Austin

# Good Afternoon, Colleagues

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- Changes from 2011 to now
- Do different formations in different situations?
- How does UT's walk engine work?
- Has the formation code been released? copied?
- Why does world model give 0s for some players? Unseen?

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- How does UT's walk engine work?
- Has the formation code been released? copied?
- Why does world model give 0s for some players? Unseen?
- Todd: Why not run CMA-ES to optimize role positions too?

# Logistics

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- Assignment 4 due today

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- Next week's readings posted

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- Final project proposal assigned

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- *Proposal (10/11):* 3+ pages
  - What you're going to do; graded on writing

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- *Progress Report (11/8)*: 5+ pages + binaries + logs
  - What you've been doing; graded on writing

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- *Progress Report (11/8)*: 5+ pages + binaries + logs
  - What you've been doing; graded on writing
- *Peer Review (11/15)*: review 2 progress reports
  - Clear? suggestions?; graded on writing and feedback quality

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  - The tournament entry; make sure it runs!

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**Due at beginning of classes**

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- Example final report on website

# Overview of the Readings

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- *MacAlpine et al*: UT Austin Villa 2011
- *Barrett et al*: SPL Kicking strategy

# Evolutionary Computation

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Some slides from *Machine Learning* (Mitchell, 1997)

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- Success of the method, but not pursued

# Architecture for Action Selection

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- (other slides, video)

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- downsides
- Keepaway

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- Why just imitate another team?

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- Why just imitate another team?
- Other slides

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- Large state space, joint actions
- Address this with state aliasing, options
- Successfully learn the task, use for some of team behavior
- However, takes 12 million actions to learn

# UT Austin Villa 2011

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- Why not use CMA-ES on role positions as well?

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- Why not use CMA-ES on role positions as well?
- Changes for 2012?

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- Emphasis on quickness

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- Adjust to seen ball location
- Select first kick that moves ball up field
- Figure
- Emphasis on quickness
- Now: Better model of opponents -> Know if we have more time

# Learning Keepaway

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## KEEPAWAY SLIDES

# Learning Commentary

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- David Chen and Ray Mooney

# Coordination Graphs

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- Coordination problem:  $R_1 = \dots = R_n = R$
- Nash equilibrium: no agent could do better given what others are doing.
- May be more than one (chicken)

# Example from the paper

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- What does it mean for  $G_3$  to maximize over all actions of  $a_1$  and  $a_2$ ?
- How are the results propagated back?
- Let's try again with  $G_1$  eliminated first

# Application to soccer

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- Assume global state information
- Finds pass sequences and starts players moving ahead of time.
- Note the results: with and without coordination.

# Reactive Deliberation

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- A hybrid approach
- Executor: carry out reactive behaviors
- Deliberator: evaluate possible high-level schema with parameters; generate bids
- Deliberator takes time, but something keeps happening always.
- In effect: deliberator commits to schema for some time