

University of West Bohemia, Pilsen
23rd February 2015



UT2004 bots made easy!

Tag! Tournament in Pogamut 3

Practical lesson

Tag! Tournament



Workshop website

On Pogamut devel wiki...

■ Visit workshop website

- http://pogamut.cuni.cz/pogamut-devel/doku.php?id=lectures:pilsen_pogamut_2014-15_summer_semester
- 1) Go to <http://pogamut.cuni.cz>
- 2) Find a link to devel wiki (<http://pogamut.cuni.cz/pogamut-devel>)
- 3) In main menu Click Lectures
- 4) Find and click a link to this years Pilsen workshop website and ...

■ Assignment Tag! Bot

- Start downloading the TagBot project template (~64MB) in advance ... now 😊

Motivation

>>> Why am I sitting here?

<<< We're going to dive into PogoMutUT2004 platform ... technically.

>>> Great, just another proprietary library...

<<< Correct, but:

<<< 1) you have to deal with them everywhere,

<<< 2) platform is created around universal principles, you will learn what to look for in other game engines.

>>> Really... *[skeptical face]*

<<< We can only show you the door, you are the one who has to go through it... ;-)



Today's menu

1. Big Picture

2. How to see

- `Self, Player, Location, Rotation, Velocity`
- `this.info, this.players`

3. How to move

- `Move, Jump, Dodge`
- `this.move`

4. Tag! Game

- `Rules, Map`
- `TagMap`

5. How to think

- `Intelligence by design`

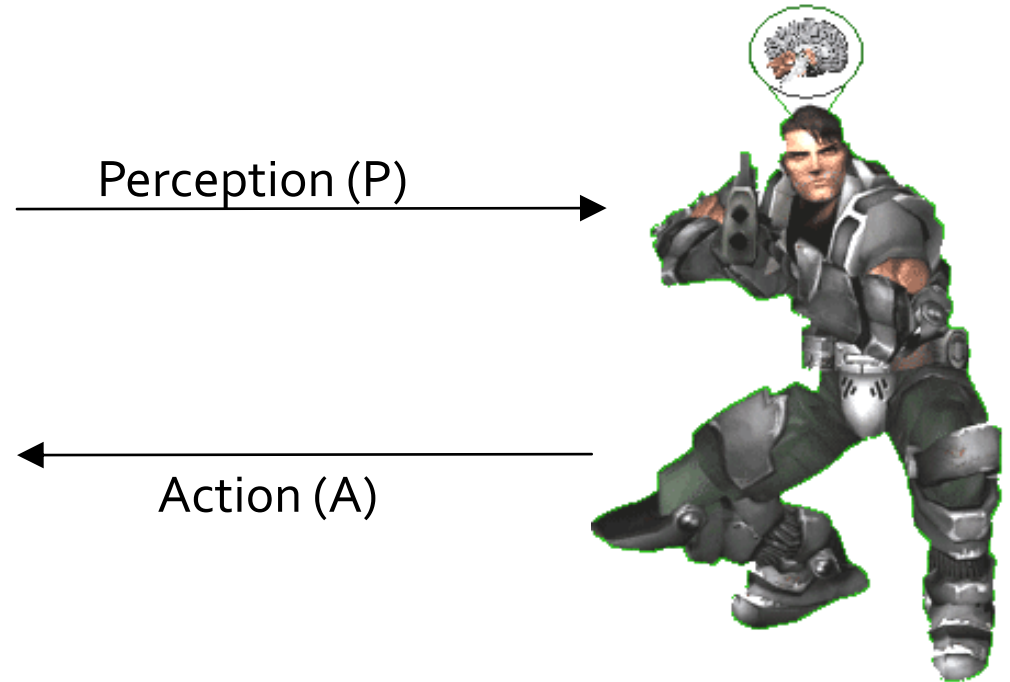
6. Tag! Tournament Announcement

Big Picture

Environment state (E)



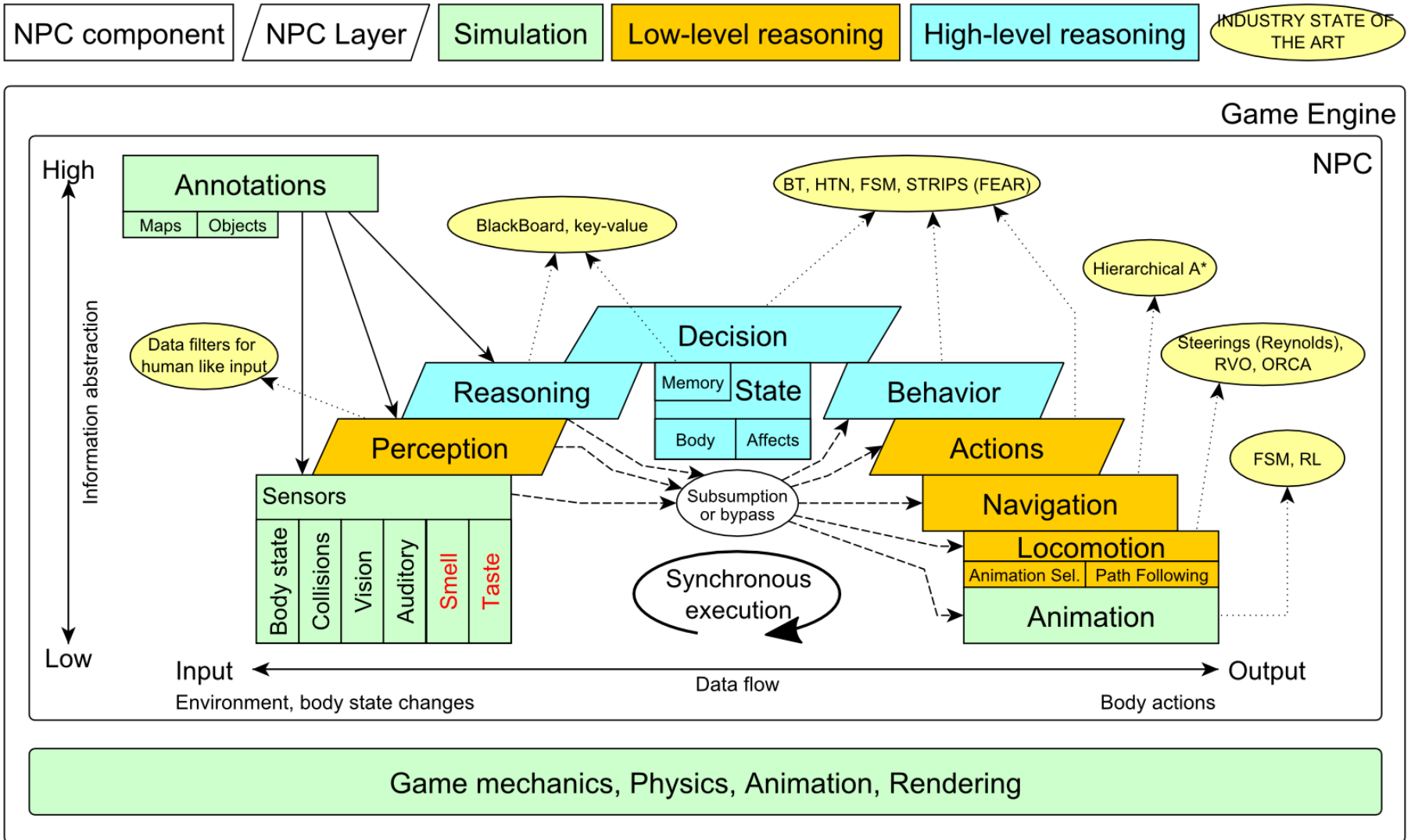
Memory (S)



1. Part of environment state E is exported to the agent $p(E) = P$
2. Agent performs action-selection: $f(P,S) \rightarrow A \times S$
3. Actions are carried out in the environment: $a(A^n, E) \rightarrow E$

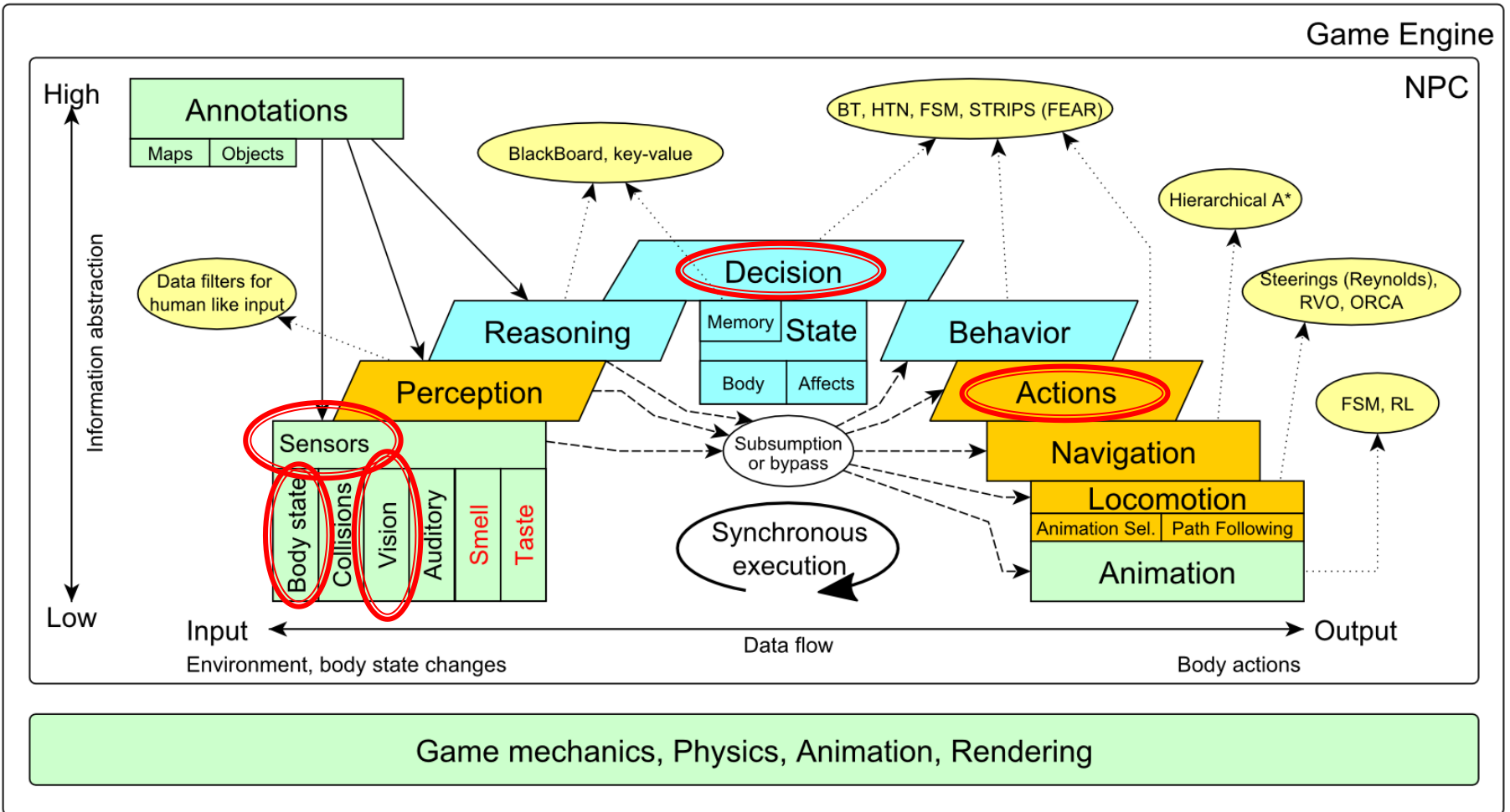
What if we dive deeper?

Big Picture



Big Picture

Today



Today's menu

1. Big Picture
2. **How to see**
 - `Self, Player, Location, Rotation, Velocity`
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How to see?

Sensors – Body state, Vision

- `IWorldObjects`
 - `Self, Player, Item, NavPoint, ...`
 - `this.world.getSingle(Self.class)`
 - `this.world.getAll(Player.class)`
 - `this.world.getAll(Item.class)`
 - `this.world.getAll(NavPoint.class)`
- Agent modules
 - `AgentInfo ~ this.info`
 - `Players ~ this.players`
 - `Items ~ this.items`
 - `NavPoints ~ this.navPoints`
- `Location, Rotation, Velocity`

How to see?

Sensors – Body state, Vision

- `IWorldObjects`
 - `Self, Player, Item, NavPoint, ...`
 - All objects have unique `UnrealId`
 - Each unique id has single `UnrealId` instance
 - Each unique object has single instance
 - Agent modules are respecting this, no sneaky `clone()`s

What does it mean for **Collections**?

=> can be used in `Set<UnrealId>, Set<Player>`

=> can be used as key in `Map<UnrealId, ?>, Map<Player, ?>` without performance hit

How to see?

Sensors – Body state, Vision

- `IWorldObjects`
 - `Self, Player, Item, NavPoint, ...`
 - All objects have unique `UnrealId`
 - Each unique id has single `UnrealId` instance
 - Each unique object has single instance
 - Agent modules are respecting this, no sneaky `clone()`s

What does it mean for **object updates**?

=> once obtained instances are auto-updated

=> there is no history

How to see?

Sensors – Body state, Vision

- `IWorldObjects` ~ low-level API
 - `this.world.getSingle(Self.class)`
 - Info about your bot
 - `this.world.getAll(Player.class)`
 - Returns `Map<UnrealId, Player>`
 - All players encountered during the session
 - `this.world.getAllVisible(Player.class)`
 - Returns `Map<UnrealId, Player>`
 - All players currently visible (in bot's FOV)
 - `this.world.getAll/Visible(Item.class)`
 - `this.world.getAll/Visible(NavPoint.class)`
 - ...

How to see?

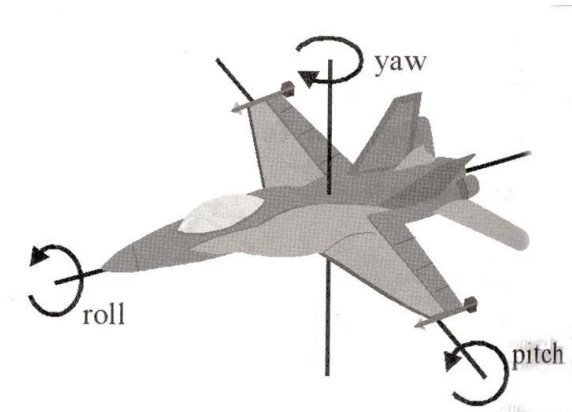
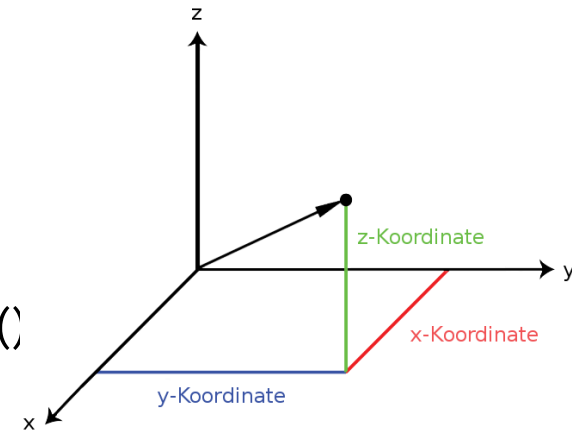
Sensors – Body state, Vision

- Agent modules ~ low-level API façades
 - AgentInfo ~ `this.info` ~ Self
 - Players ~ `this.players` ~ Player(s)
 - Items ~ `this.items` ~ Item(s)
 - NavPoints ~ `this.navPoints` ~ NavPoint(s)
- Advantages:
 1. List of methods with JavaDoc
=> Easier to way to explore Pogamut API
 2. Comprehensibly named methods
=> Easier to read & understand the code

How to see?

Sensors – Body state, Vision

- Location
 - X, Y, Z
 - can be used as “vector”
 - `add()`, `sub()`, `scale()`, `getDistance()`, `dot()`, `cross()`
 - `rotateXY/XZ/YZ()`
- Rotation
 - Pitch (XZ), Yaw (XY), Roll (YZ)
- Velocity
 - X, Y, Z
- All objects are immutable
=> Can be used in Set, Map



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 - Intelligence by design
6. Tag! Tournament Announcement

How to move?

Actions

- CommandMessages
 - Move, Jump, Dodge
 - `this.act.act(new Move())...`
 - `this.act.act(new Jump())...`
 - `this.act.act(new Dodge())...`
- Agent module
 - `AdvancedLocomotion ~ this.move`

How to move?

Actions

- `CommandMessages` ~ low-level API
 - Move
 - You can specify 1 location in advance
 - You can specify focus (where to look while moving), i.e., can be used for strafing
 - Jump
 - Can be used for double-jumps as well
 - Dodge
 - Can be used for quick direct jump to arbitrary location

How to move?

Actions

- Agent modules ~ low-level API façade
 - `AdvancedLocomotion` ~ `this.move`
 - All commands wrapped into methods
 - `move.moveTo()`, `move.strafeTo()`, `move.jump()`, ...
 - Some simple algebra wrapped as well
 - `move.dodgeLeft()`, `move.dodgeRight()`, ...

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Tag! Game

Children play

- Custom “game-mode” for UT2004
- Two roles:
 1. Seeker (having “it”)
 2. Runner or Prey
- Seeker has to chase runners to pass „it”
- After passing “it” the *former* seeker is immune to the *new* seeker
- `this.tag` agent module
- Custom map: DM-TagMap
 - Simple rectangle map, no obstacles
 - procedurally described by `TagMap` static methods

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How to think?

Intelligence by design

Environment state (E)



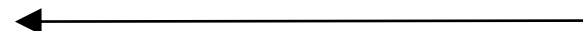
Perception (P)



Memory (S)



Action (A)



1. Part of environment state E is exported to the agent $p(E) = P$

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How to think?

Intelligence by design

Behavior Oriented Design

by Joanna J. Bryson (UK)

<http://www.cs.bath.ac.uk/~jjb/web/bod.html>

1. Specify top-level decision
 - a) Name the behaviors that the bot should do
 - b) Identify the list of sensors that is required to perform the behavior
 - c) Identify the priorities of behaviors
 - d) Identify behavior switching conditions
2. Recursion on respective behaviors until primitive actions reached

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Tag! Tournament

Chance to earn honor and glory!

- 4 bots
 - 1 Seeker, 3 Runners (1 of them will be immune...)
- Random groups
- No shooting allowed, no bot speed reconfigurations allowed
- Details will be announced
 - When, where, how...
- The best N bots from previous Tag! Tournament will participate?
 - You will have a chance to test your bots against them in advance

Assignment Tag! Bot

- Download the TagBot project template
- Copy `map/DM-TagMap.ut2` into `UT2004/Maps` folder
- Alter
`UT2004/System/startGamebotsDMServer.bat`
replacing `DM-TrainingDay` with `DM-TagMap`
- Implement both TagBot roles
 - Seeker
 - Runner
- Implementations having one role only won't be accepted for the tournament

Assignment Tag! Bot

- Note that there are two “main” Java files in the project
- TagBot
 - Bot template you have to finish
 - **DO NOT ALTER ITS main METHOD!**
- TagGame
 - Class that starts the match between 4 your bots
 - Use this to test your bot

Assignment Tag! Bot

Extra Tournament Files

- Check the folder `TagBot/tournament`
- There are batch files to execute tournament matches
 - `match-best-2013.bat`
 - Performs match between the first 4 bots of the Tag! 2013
 - `match-123.bat`
 - Performs match between your bot and 1st, 2nd and 3rd bot of Tag! 2013
 - `match-456.bat`
 - Performs match between your bot and 4th, 5th and 6th bot of Tag! 2013

Assignment Tag! Bot

Extra Tournament Files

- **WARNING!** You have to edit batch files first, to supply correct `UT2004_HOME` directory
- Alter the line
`set UT2004_HOME=d:\Games\UT2004-Devel`
- To match your environment, e.g.
`set UT2004_HOME=c:\UT2004`

Assignment Tag! Bot

Extra Tournament Files

- **WARNING!** Execution of the batch file might override you bot/server ports within `UT2004_HOME\System\GameBots2004.ini`
 - You might bump into “connection refused” exceptions when trying to run your bot from `TagGame` of the template project
- Just restore original values within the `GameBots2004.ini` file, and restart a dedicated server:

```
[GameBots2004.BotDeathMatch]
BotServerPort=3000
ControlServerPort=3001
ObservingServerPort=3002
```

Assignment Tag! Bot

Extra Tournament Videos

- Check the folder `TagBot/tournament-videos`
- There are several videos that might inspire you for coding Seeker/Runner behaviors

Send us finished assignment

Via e-mail:

- *Subject*
 - "Pogamut Pilsen 2015 – Tag Bot"
 - Replace 'X' with the assignment number and the subject has to be without quotes of course
 - ...or face **-2 score penalization (I mean our wrath)**
- *To*
 - jakub.gemrot@gmail.com
 - Jakub Gemrot
- *Attachment*
 - Completely zip-up your project(s) folder except 'target' directory and IDE specific files (or face **-3 score penalization (even greater wrath)**)
- *Body*
 - **Please send us information about how much time it took you to finish the assignment + any comments regarding your implementation struggle**
 - *Information won't be abused/made public*
 - *In fact it helps to make the practice lessons better*
 - Don't forget to mention your full name!

Questions?

I sense a soul in search of answers...

- We do not own the patent of perfection (yet...)
- In case of doubts about the assignment, tournament or hard problems, bugs don't hesitate to contact us!
 - Jakub Gemrot
 - jakub.gemrot@gmail.com
 - Michal Bída
 - michal.bida@gmail.com