



W o M P - 2 0 1 2

THE 1ST WORKSHOP
ON
MULTIAGENT
PATHFINDING

AAAI 2012 Workshop, Toronto, Canada



Technical Program

09:00:00	Introduction, history and terminology
09:30:00	Independence Detection for Multi-Agent Pathfinding Problems
10:00:00	Conflict-Based Search For Optimal Multi-Agent Path Finding
10:30:00	Coffee break
11:00:00	Non-optimal Multi-Agent Pathfinding is Solved (Since 1984)
11:30:00	Positioning to Win: A Dynamic Role Assignment and Formation Positioning System
12:00:00	
12:30:00	Lunch
13:00:00	
13:30:00	Time Optimal Multi-agent Path Planning on Graphs
14:00:00	Towards Using Discrete Multiagent Pathfinding to Address Continuous Problems
14:30:00	Poster Highlights (10 min. per poster)
15:00:00	
15:30:00	Poster session
16:00:00	Coffee break
16:30:00	Reciprocal Collision Avoidance and Multi-Agent Navigation for Video Games
17:00:00	Reciprocal Collision Avoidance for Quadrotor Helicopters using LQR-Obstacles
17:30:00	
18:00:00	Conclusion and discussions

Posters

1	DEC-A*: a decentralized A* algorithm (Mohamad El Falou, Bouzid Maroua and Abdel-Ilhah Mouaddib)
2	Learning conflicts from experience (Yann-Michaël De Hauwere and Ann Nowé)
3	Towards optimization-based multi-agent collision-avoidance under continuous stochastic dynamics (Jan Calliess, Michael Osborne and Stephen Roberts)
4	Towards Decentralized Waypoint Negotiation (Shawn Adams and Matthew Rutherford)
5	A new approach to cooperative pathfinding (M. Renee Jansen, Nathan R. Sturtevant)
6	A* variants for Optimal Multi-Agent Pathfinding (Meir Goldenberg, Roni Stern, Ariel Felner and Jonathan Schaeffer)