

## Distributed Search Aspects

- ▶ **Mobile agents:** robots, software pieces, etc.
- ▶ **Environment:** discrete (graph) or continuous (Euclidean)
- ▶ **Tasks:** exploration, rendezvous, evacuation, patrolling
- ▶ **Communication:** wireless (global), face-to-face (local), pebbles
- ▶ **Capabilities:** speed, energy, environment dynamicity

## Our Problem: Fast Evacuation

- ▶ Two robots: Fast and Slow
- ▶ Unit disk environment
- ▶ Robots initially at center, move within disk
- ▶ Unknown exit on boundary; identified only when on it
- ▶ Instantaneous communication: once exit found, beeline
- ▶ Fast with speed  $s \geq 1$ , Slow with speed 1

## A First Strategy: Both-to-the-Same Point [1]

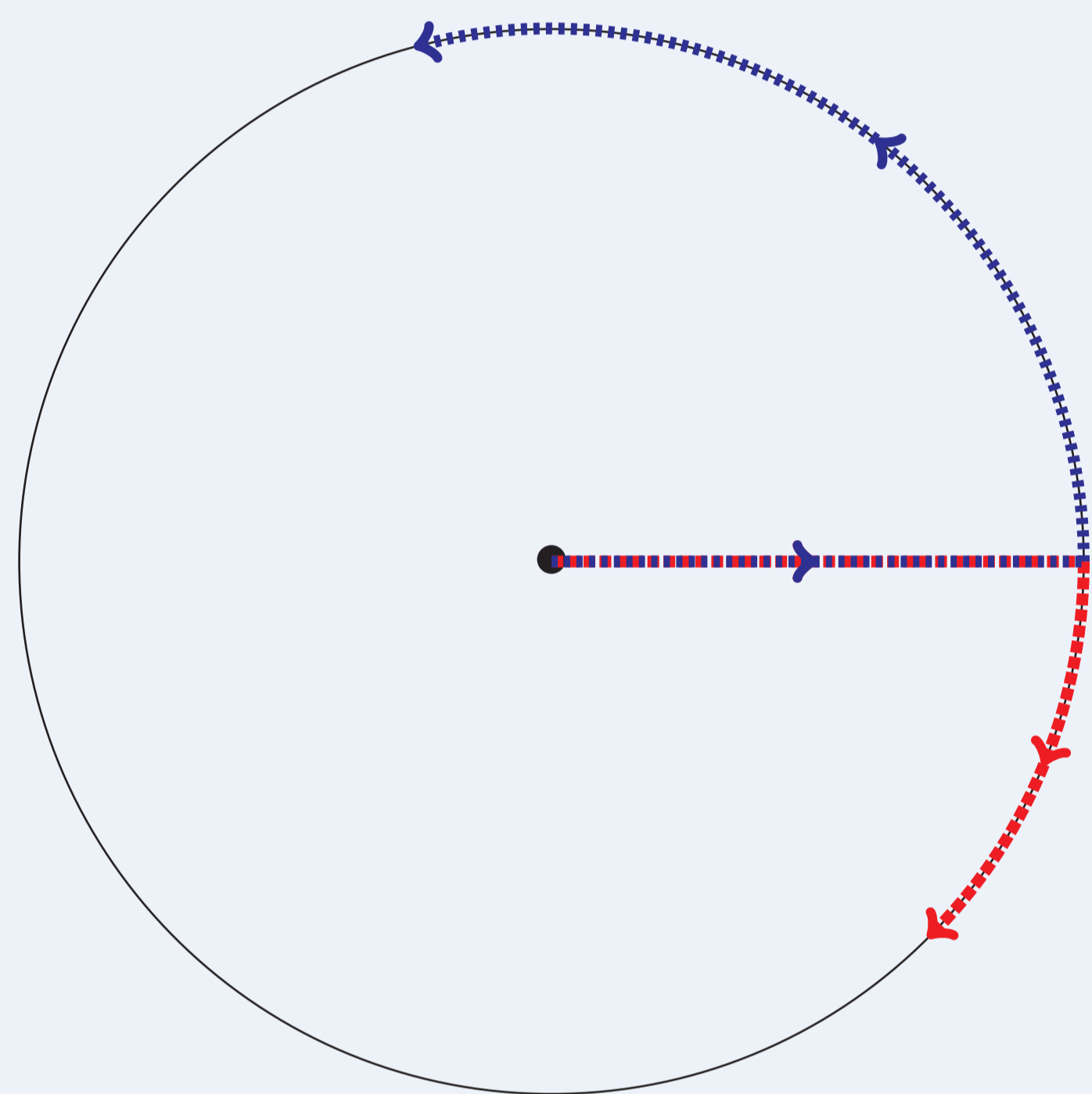


Figure 1: The **BSP** Strategy

- ▶ Fast and Slow trajectories
- ▶ Both-Explore Strategy
- ▶ Both to the same boundary point; explore in opposite directions
- ▶ Optimal for case  $s = 1$

## A Better Strategy: Half-Chord

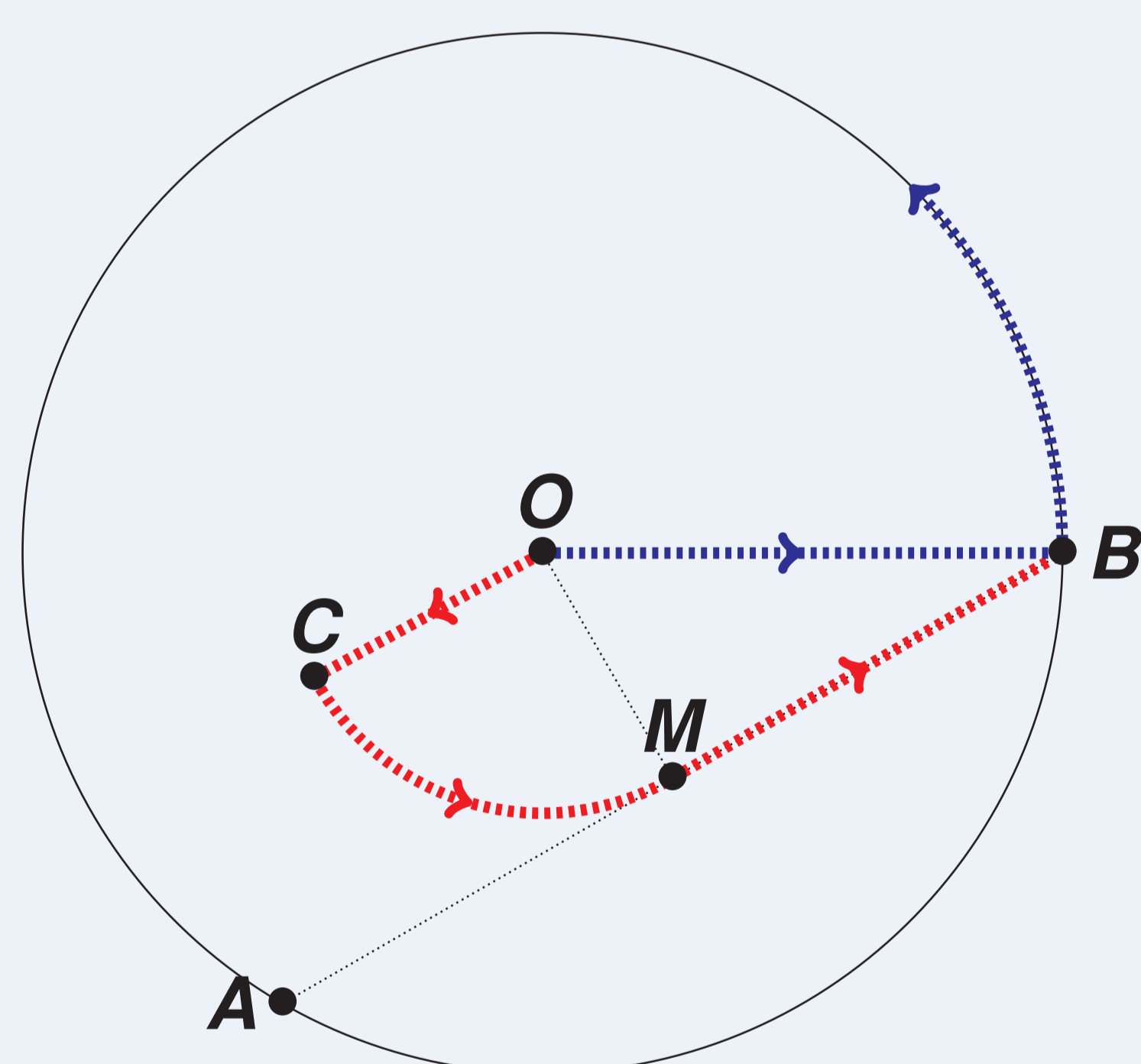


Figure 2: The Half-Chord Strategy (Example for  $s = 4$ )

### The Strategy

- ▶ Fast explores counterclockwise
- ▶ Slow takes a  $\frac{2}{s}$  radius to C, then  $\widehat{CM}$ , then half-chord MB
- ▶ Slow on M exactly when Fast on A
- ▶ Finally on B at the same time

### Lemma

**HC** outperforms **BSP** for  $s \geq 1.86$

## An Extra Improvement: Fast-Chord

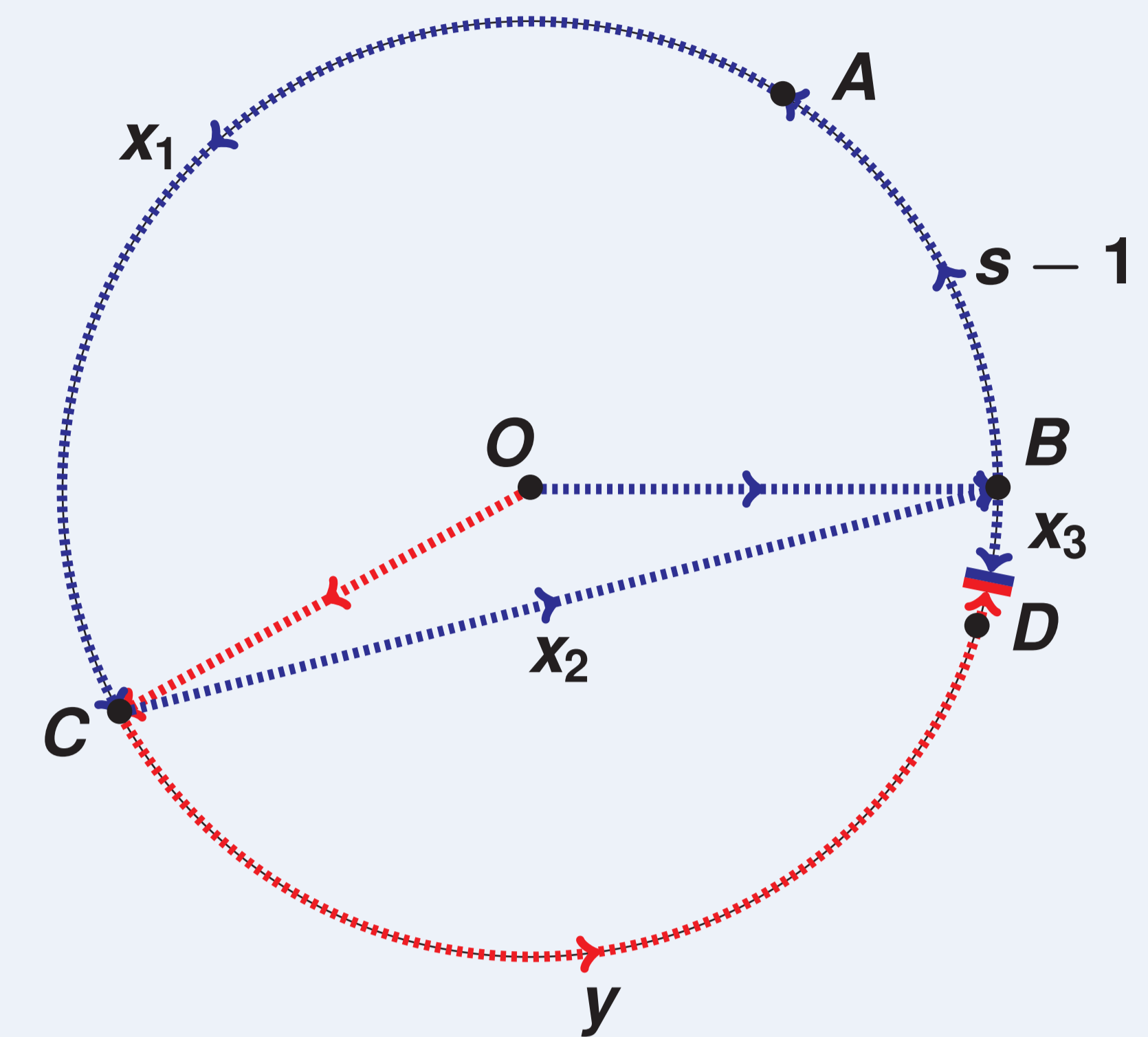


Figure 3: The Fast-Chord Family of Strategies

### The Strategy

- ▶ **HC** near  $s = 2$  forces some double exploration
- ▶ Fast follows **CB**; only Slow explores  $\widehat{CD}$
- ▶ Fast on B exactly when Slow on D
- ▶ Experiment with  $|DB|$

### Lemma

**FC** outperforms **HC** for  $1.71 \leq s \leq 2.07$

## Lower Bounds

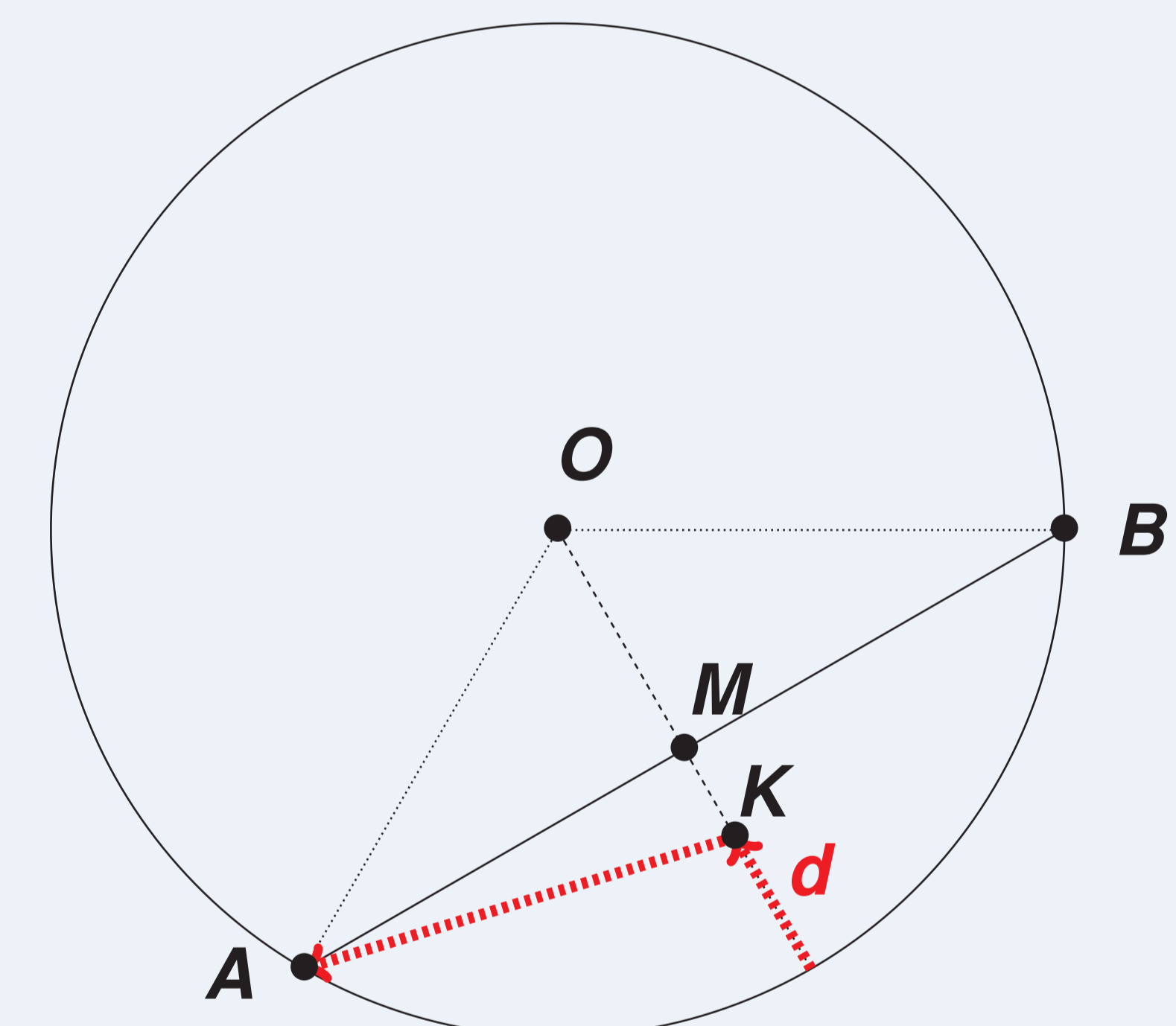


Figure 4: A Lower Bound Depiction

### The idea

- ▶ Long chord with unexplored endpoints
- ▶ When one explored, adversary places exit on the other
- ▶ Slow may be  $d$  away from boundary; covers at least  $|AK|$

### Theorem

**HC** optimal for  $s \geq 2.75$ ; ratio  $\leq 1.22$  for  $s < 2.75$

## Further Work

- ▶ Optimality for  $s < 2.75$
- ▶ More than two robots
- ▶ Face-to-face communication

## References

- [1] J. Czyzowicz et al. Evacuating robots from an unknown exit located on the boundary of a disk, *DISC 2014*, LNCS 8784, pp. 122-136, Springer, 2014.