

# Regulating Highly Automated Robot Ecologies: Insights from Three User Studies

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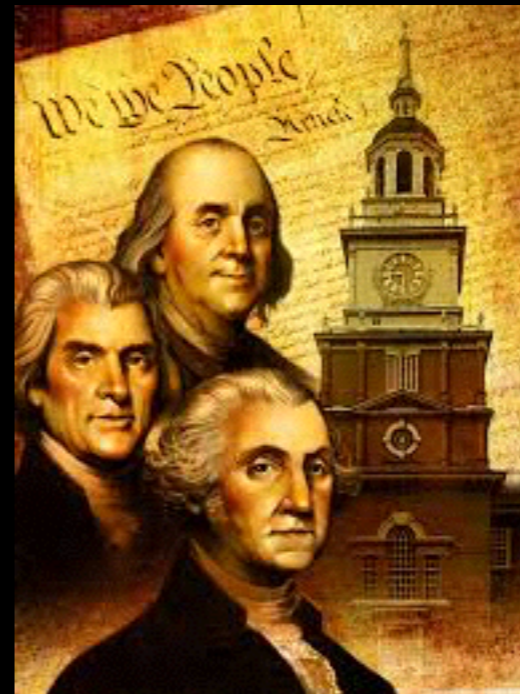
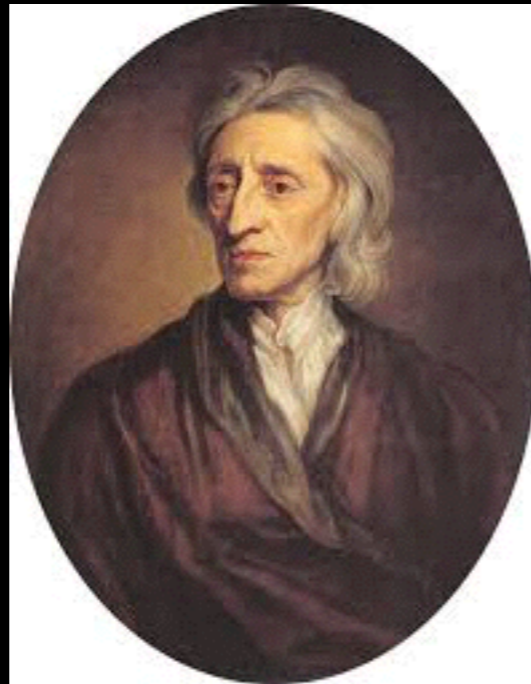
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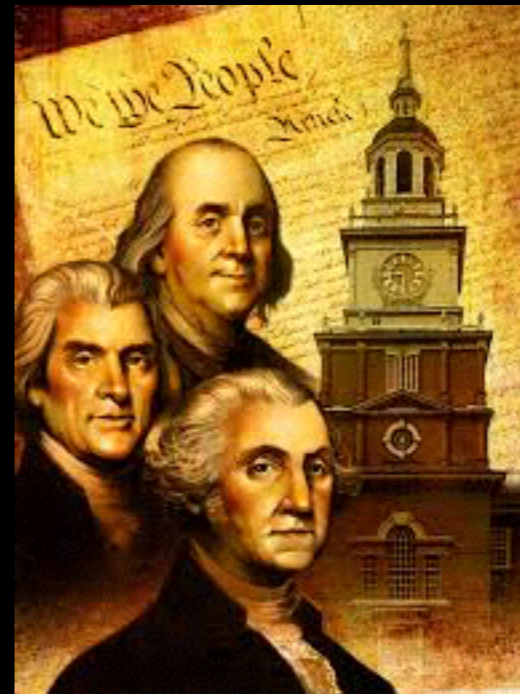
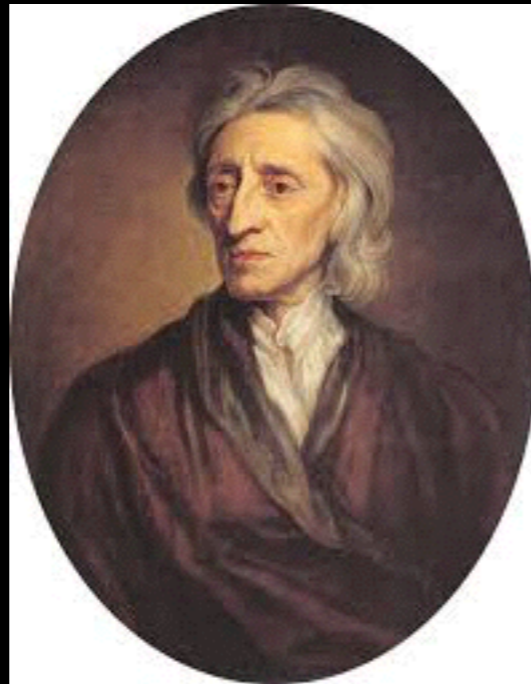
# Human Societies

- How do we achieve good human societies?



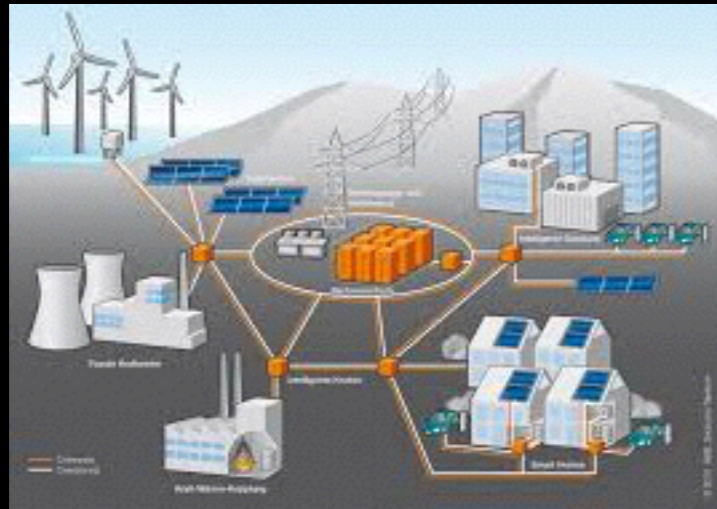
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- How do we achieve good human societies?



Strong central authority vs. strong individual rights

# Societies of Robots?



Robotic buildings  
connected via a smart grid



Self-driving cars

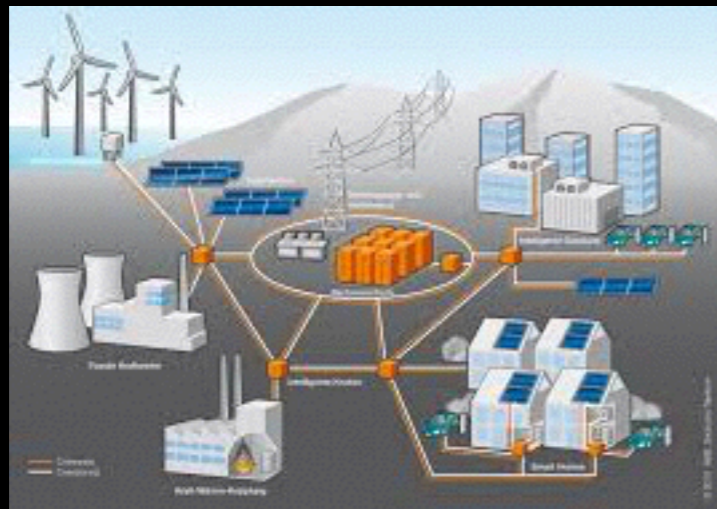


Financial Markets

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Financial Markets

Strong central authority vs. strong individual rights

# Highly **A**utomated **R**obot **E**cologies

- Society of robots or systems
  - Robots are **independent** — owned by different stakeholders
  - Robots are **autonomous** (from the perspective of the regulator)

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How can such systems be “designed”  
to produce good societal outcomes?

HARE are like what?



# HARE are like what?

Supervisory control systems

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Supervisory ~~control~~ systems

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Human Society

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Mechanism design problem

# HARE are like what?

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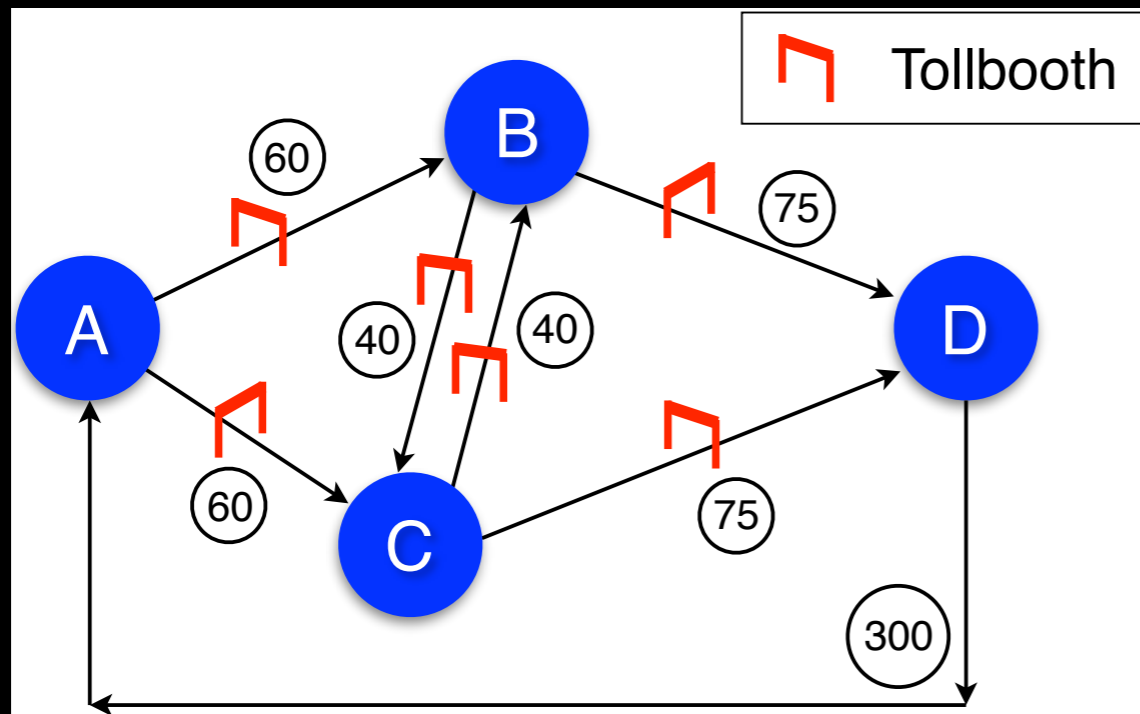
~~Mechanism design problem~~

# Challenge: Design efficient HARE

2 “design parameters”

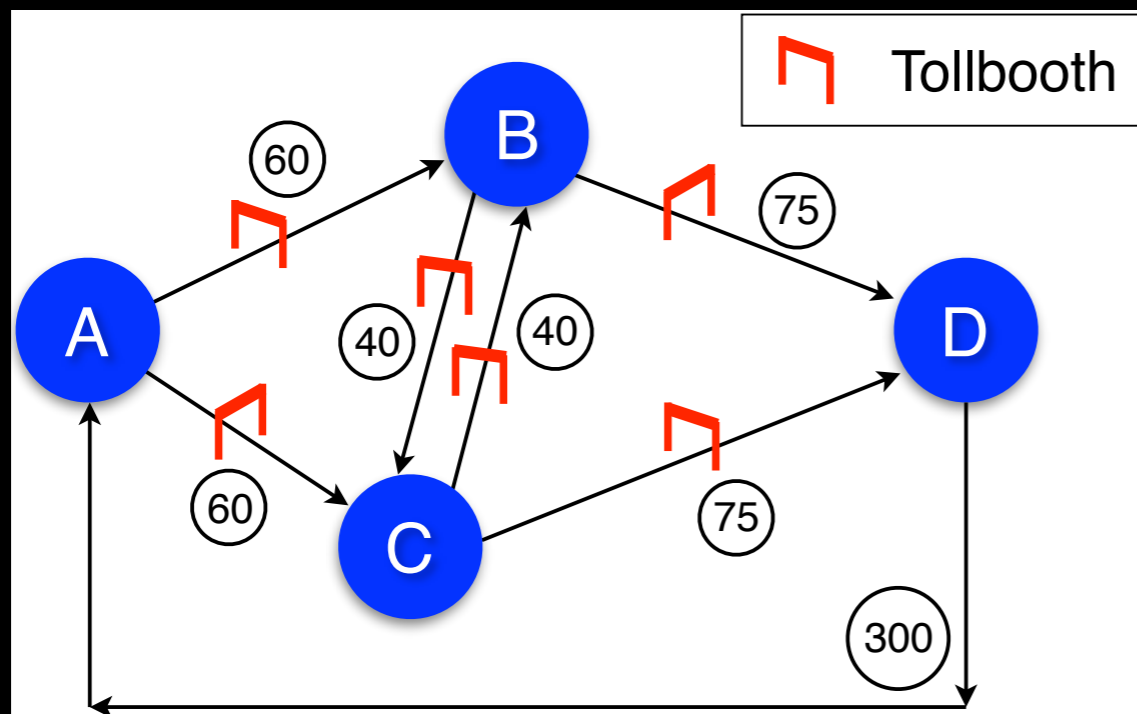
- Regulatory power
- Robot autonomy (adaptability)

# Example: Routing Game



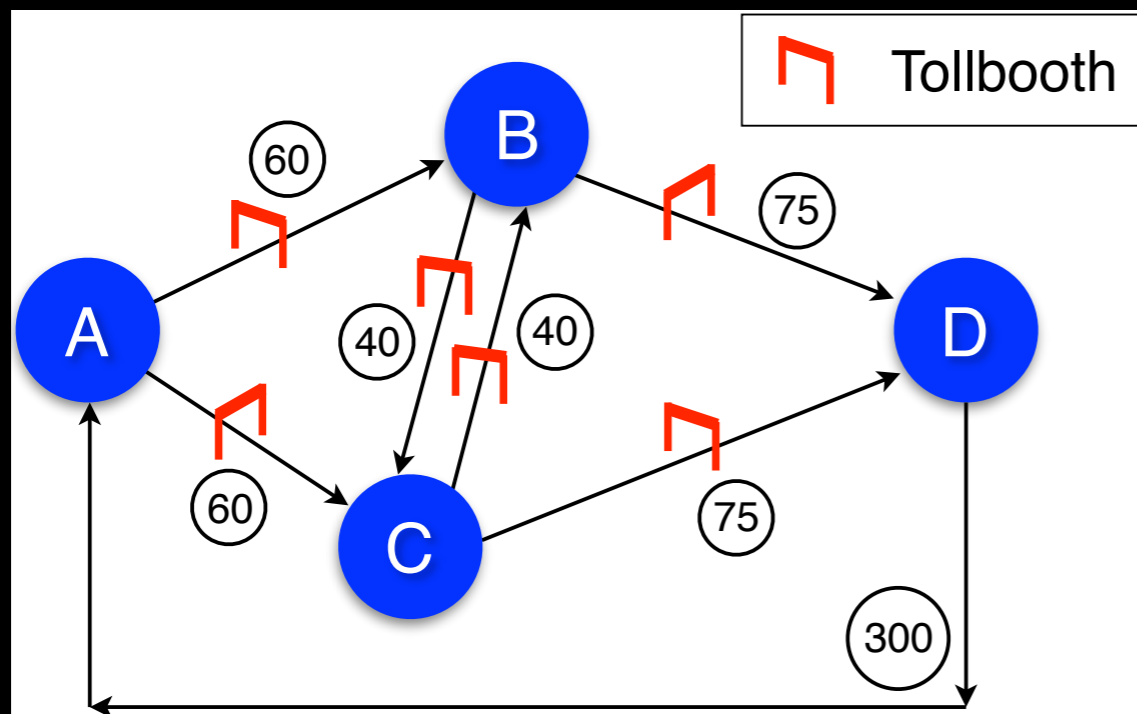


# Example: Routing Game



$$V_{ij} = f(N_{ij}, C_{ij})$$

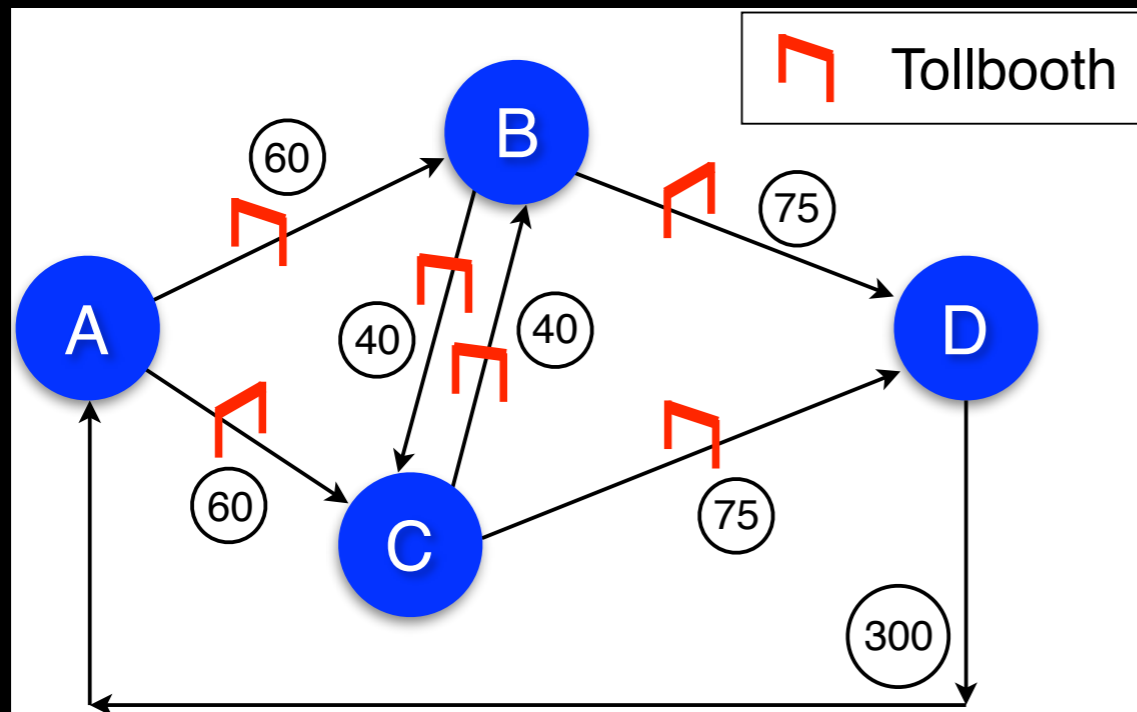
# Example: Routing Game



$$V_{ij} = f(N_{ij}, C_{ij})$$

# of vehicles  
on link i-j

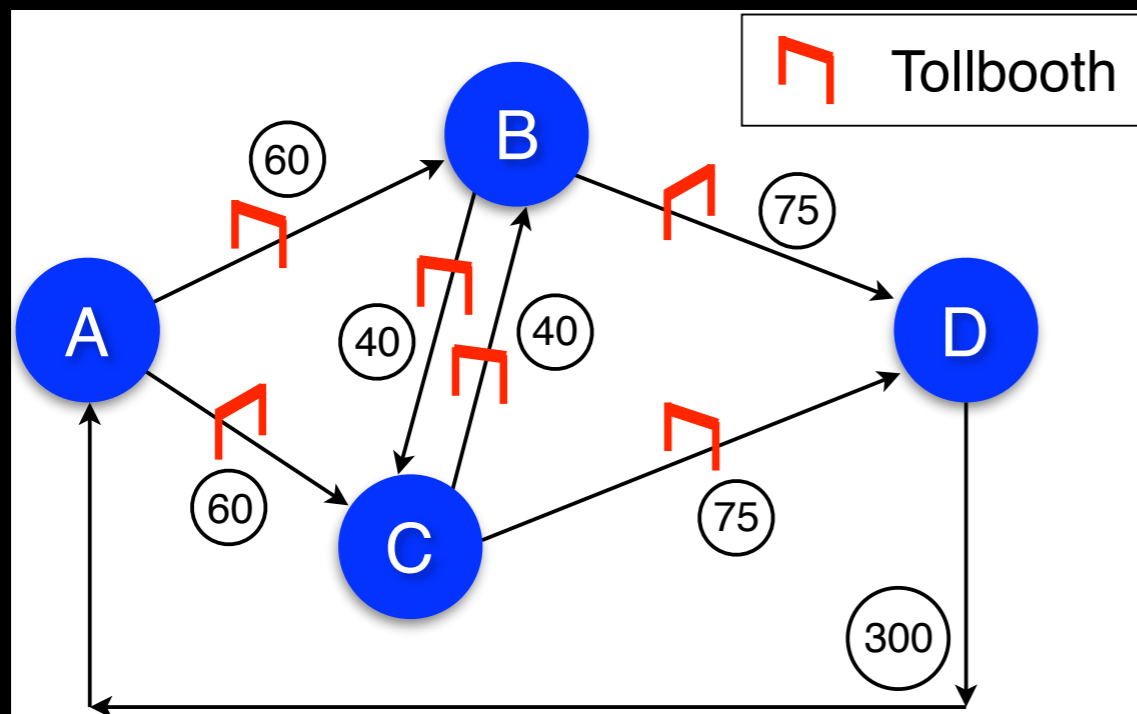
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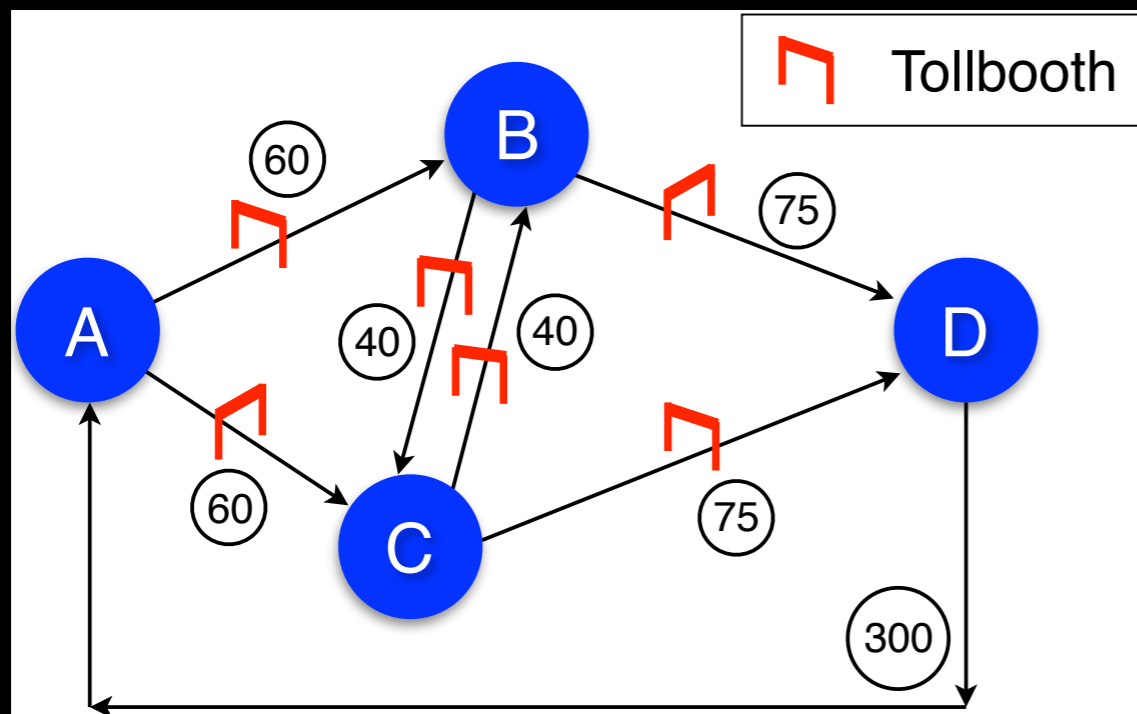
# of vehicles on link i-j      capacity of link i-j

# Example: Routing Game



$$V_{ij} \propto \frac{1}{1 + e^{0.25(N_{ij} - C_{ij})}} + 0.1$$

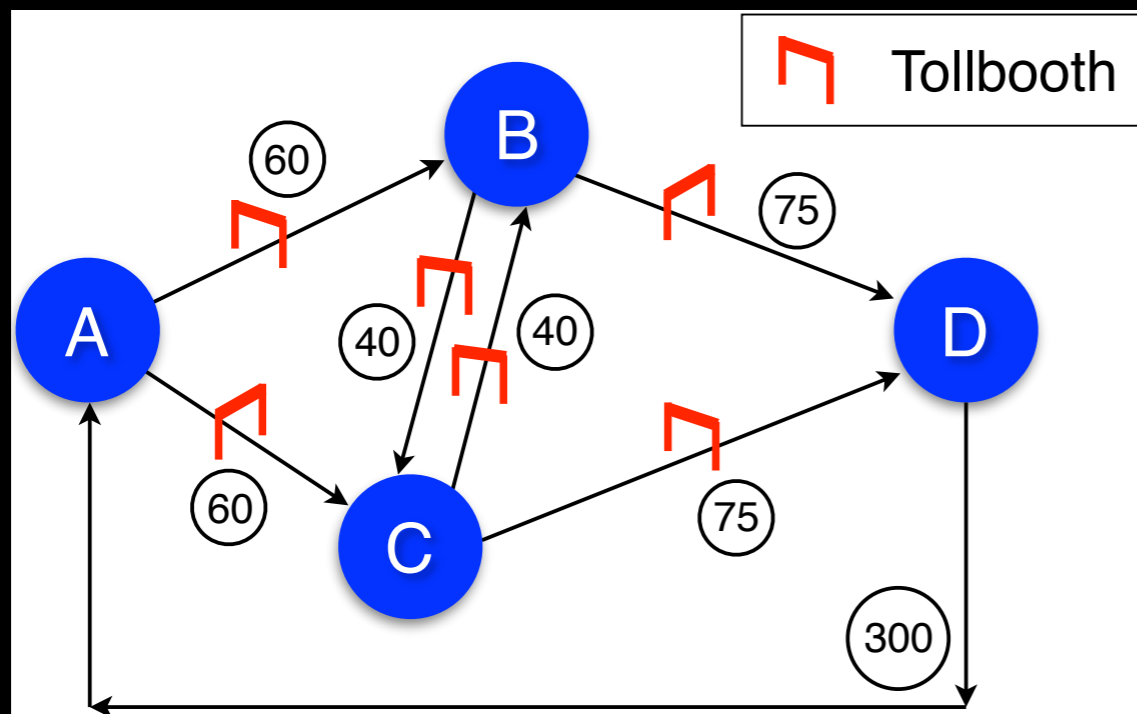
# Example: Routing Game



Regulator's Goal:  
Maximize throughput  
through node D

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# Example: Routing Game

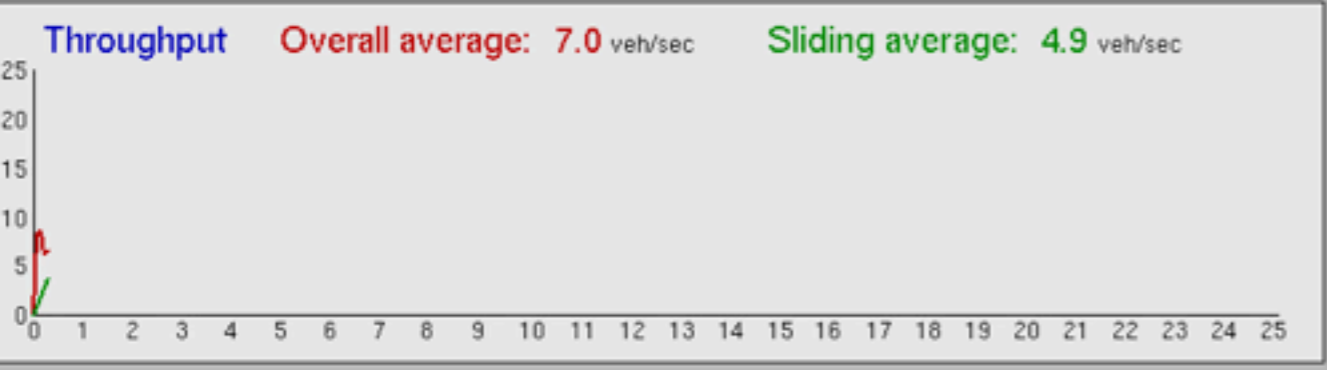


Regulator's Goal:  
Maximize throughput  
through node D

Needs to remove  
traffic congestion

$$V_{ij} \propto \frac{1}{1 + e^{0.25(N_{ij} - C_{ij})}} + 0.1$$

00:21



**High Scores**

1.	005	14.93
2.	Bill	14.71
3.	07	13.49
4.	08	13.37
5.	017	13.33

**Your Score:** \$ 6.95 / sec

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Robot Autonomy (2 levels)

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Travel  
Cost

Toll  
Cost

## Robot Autonomy (2 levels)

- **Simple** — Estimate  $c_t(i, g)$  assuming no congestion

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$$u(i, g) = v(g) - c_t(i, g) - c_{\$}(i, g)$$

Value of  
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node  $g$

Travel  
Cost

Toll  
Cost

## Robot Autonomy (2 levels)

- **Simple** — Estimate  $c_t(i, g)$  assuming no congestion
- **Adaptive** — Estimate  $c_t(i, g)$  using reinforcement learning



# Regulatory Power

Regulator's ability to change tolls

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**3 levels**

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Regulator's ability to change tolls

## 3 levels

- **None** — Regulator can do nothing
- **Limited** — Regulator can make limited toll changes
- **Unlimited** — Regulator can make unlimited toll changes

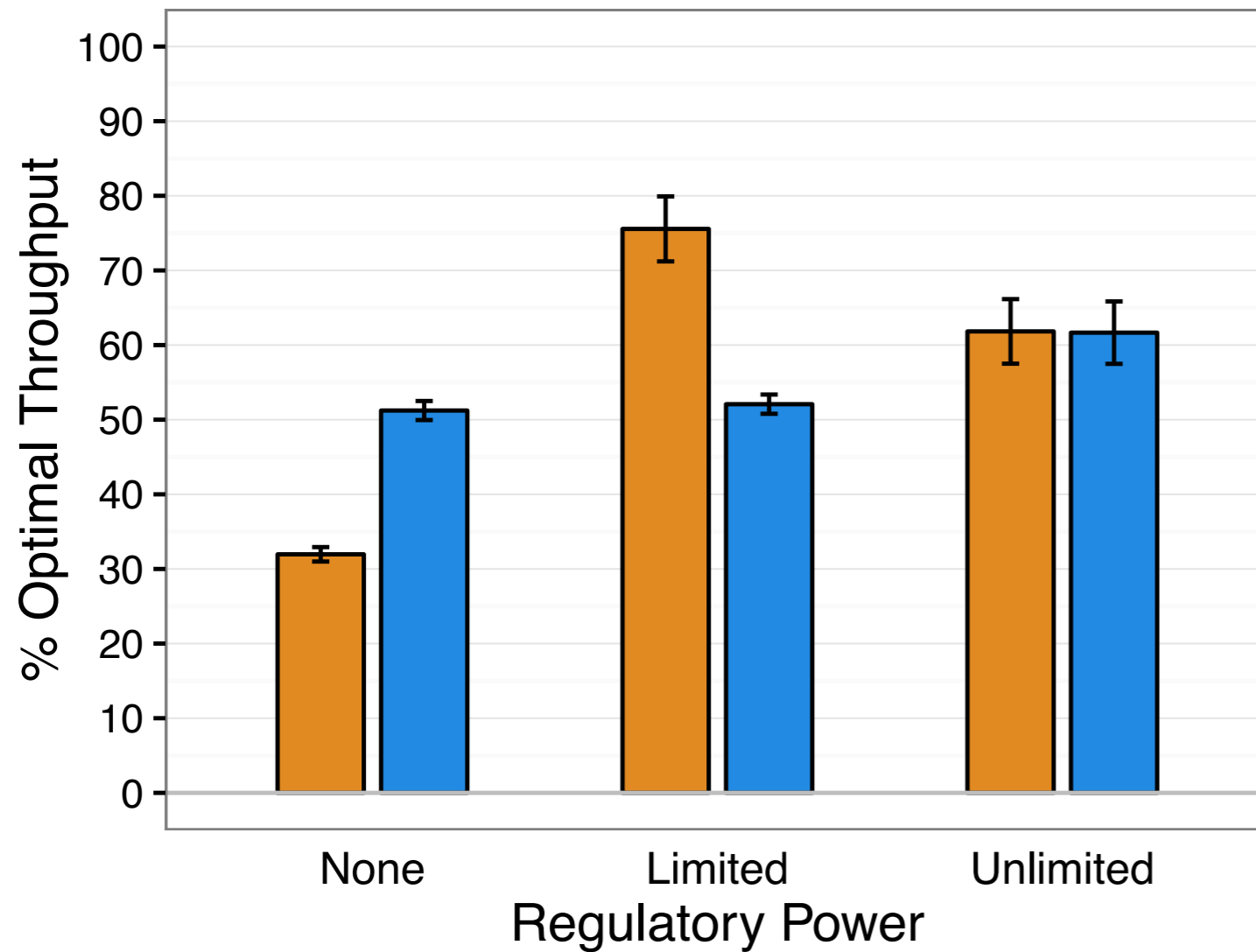
# Experimental Setup

		Regulatory Power		
		None	Limited	Unlimited
Algorithmic Sophistication	Simple			
	Adaptive			

Which one will be best?

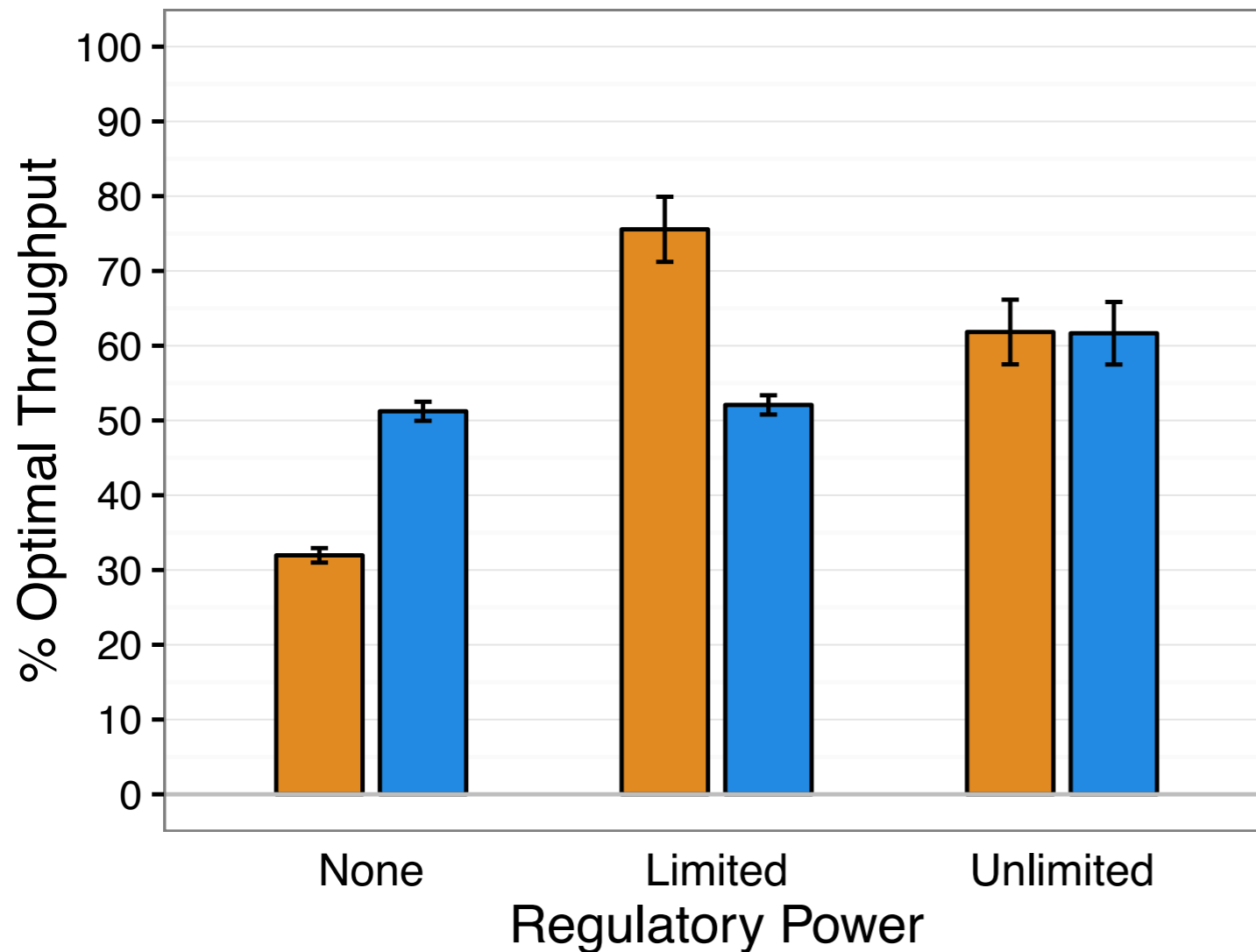
# Outcome

Simple automation Adaptive automation



# Outcome

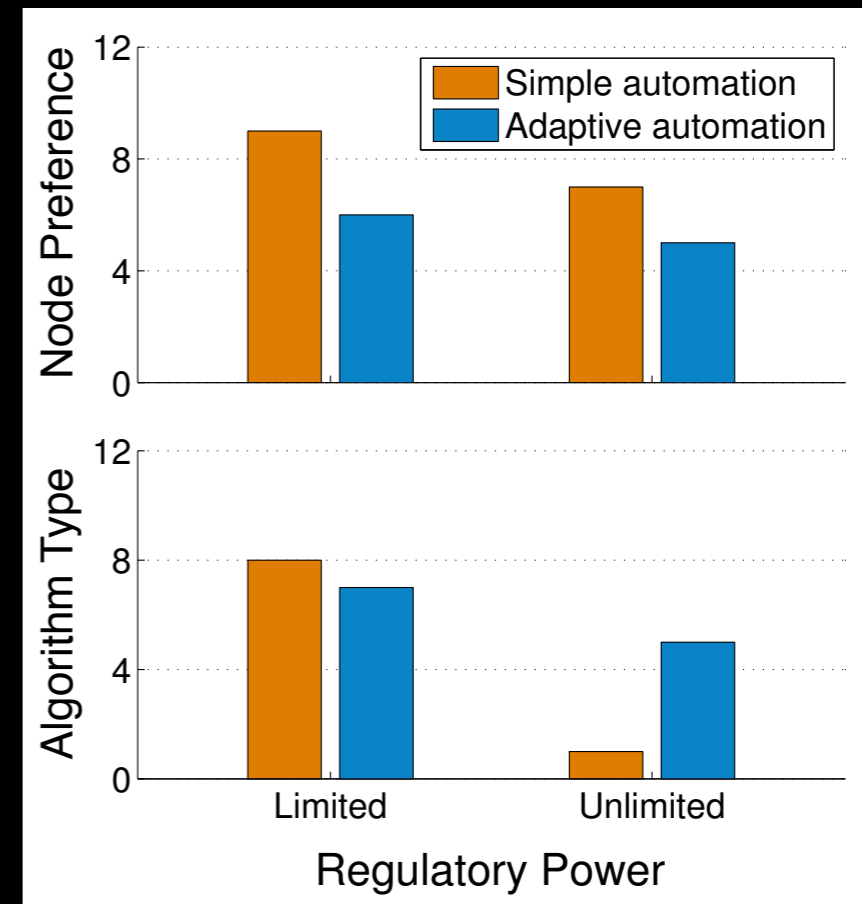
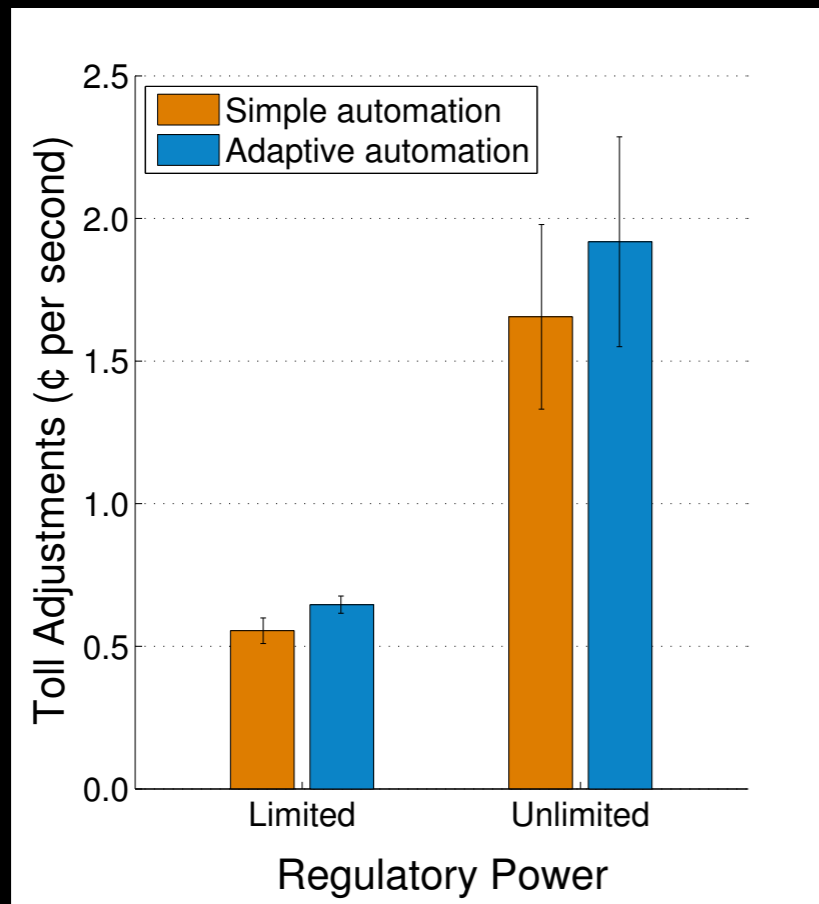
Simple automation Adaptive automation



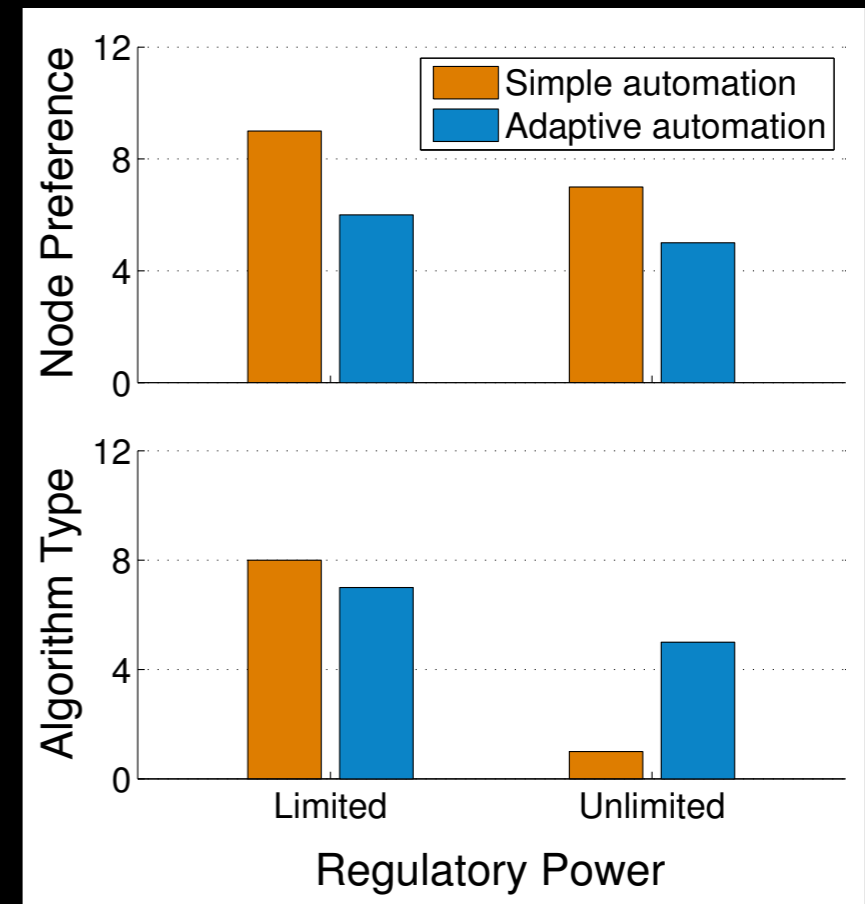
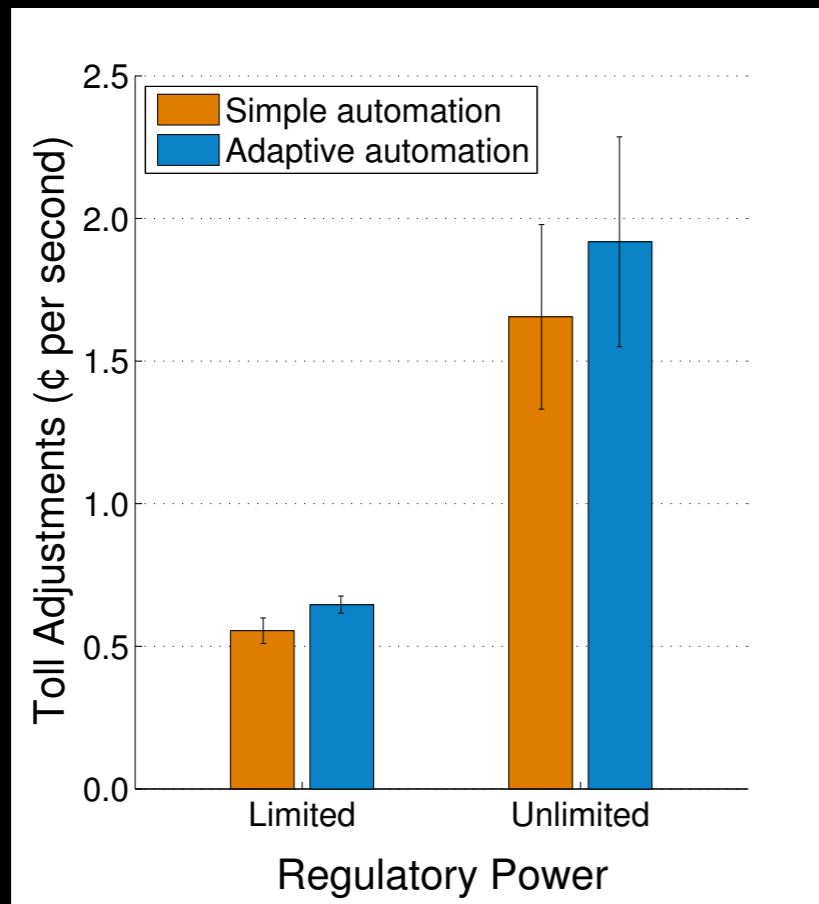
		Regulatory Power		
		None	Limited	Unlimited
Algorithmic Sophistication	Simple	6	1	T2
	Adaptive	T4	T4	T2



# Why Simple-Unlimited?

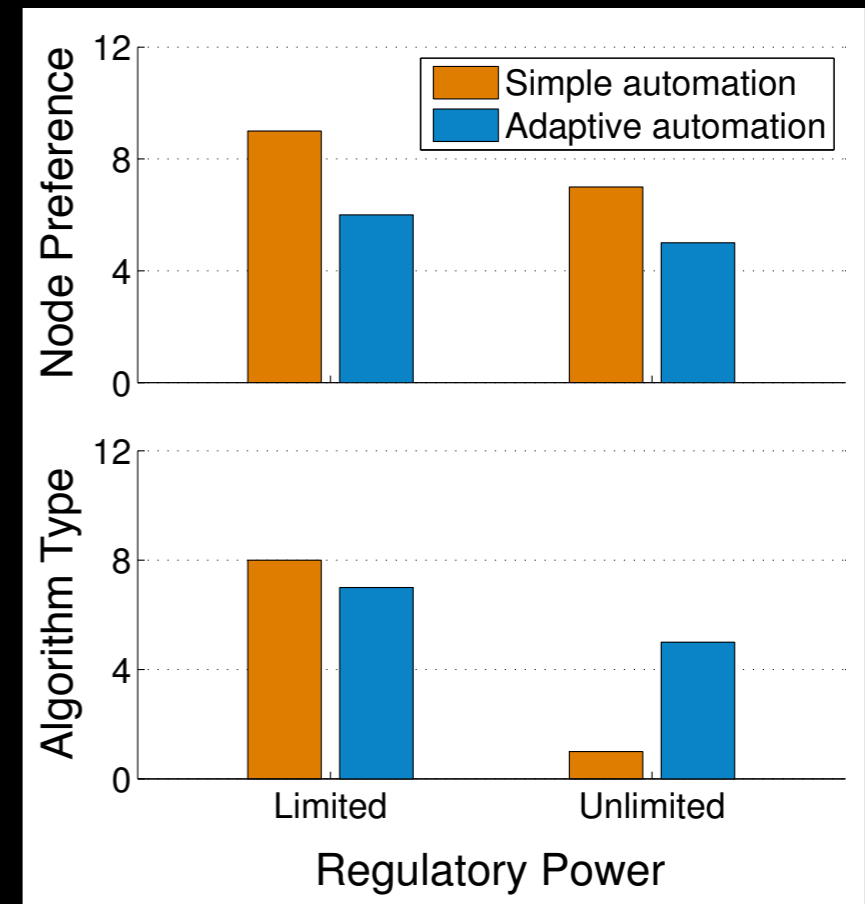
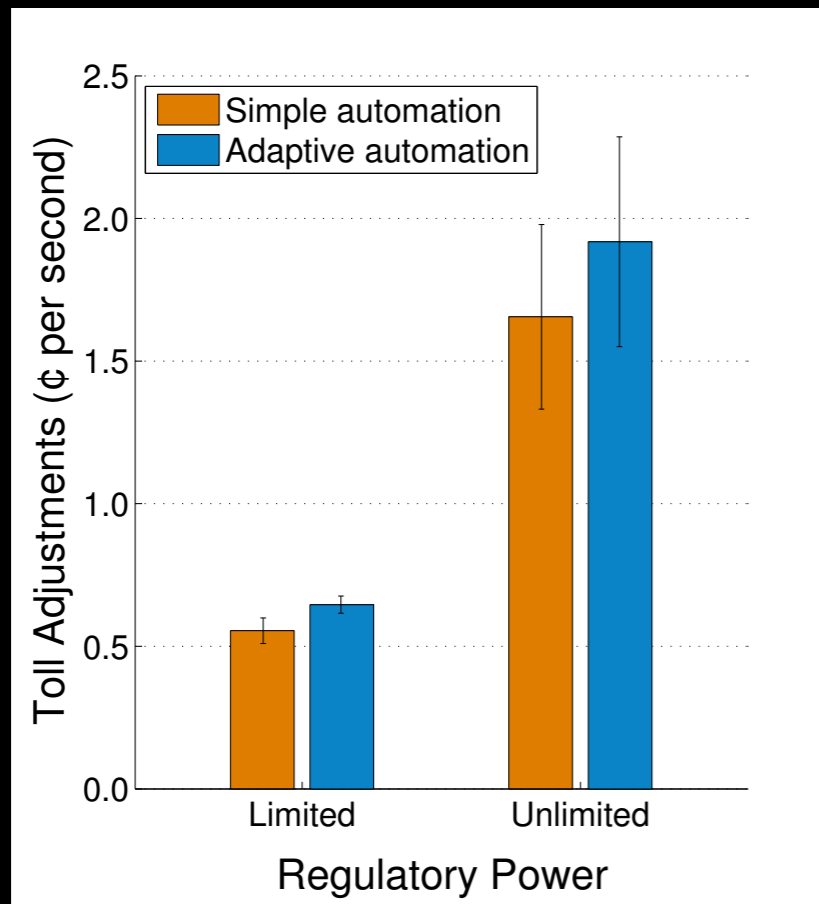


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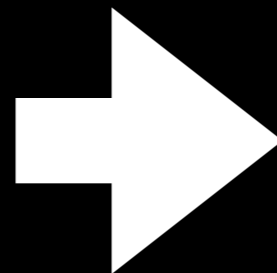


Given Unlimited Power,  
Regulators used power  
they didn't need

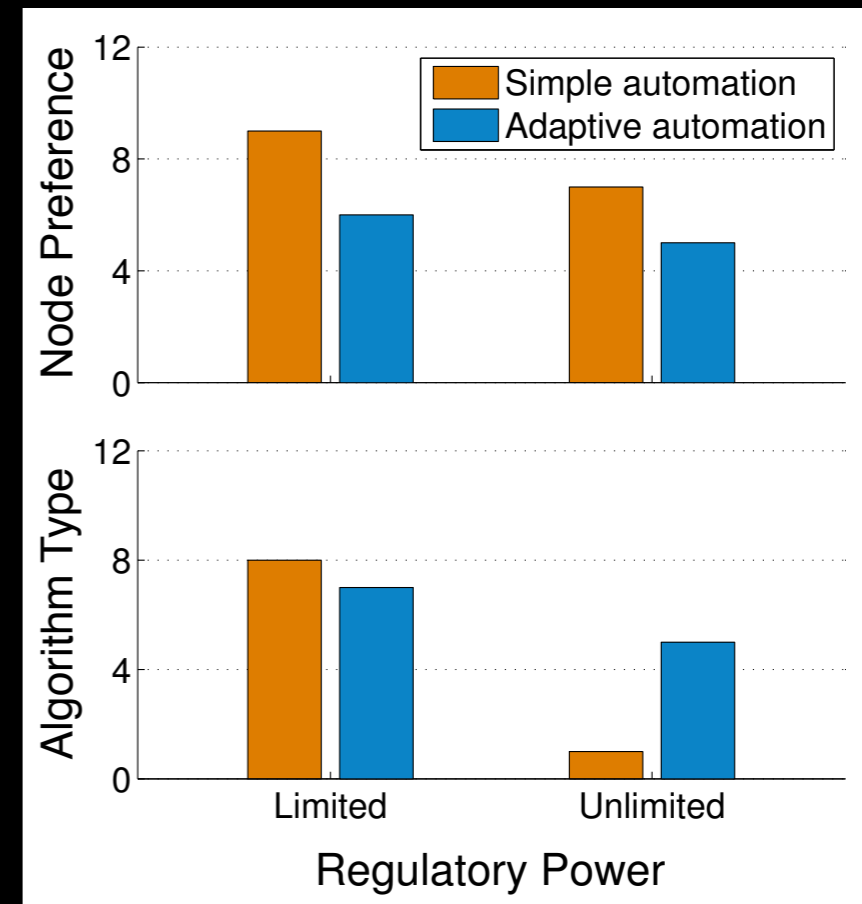
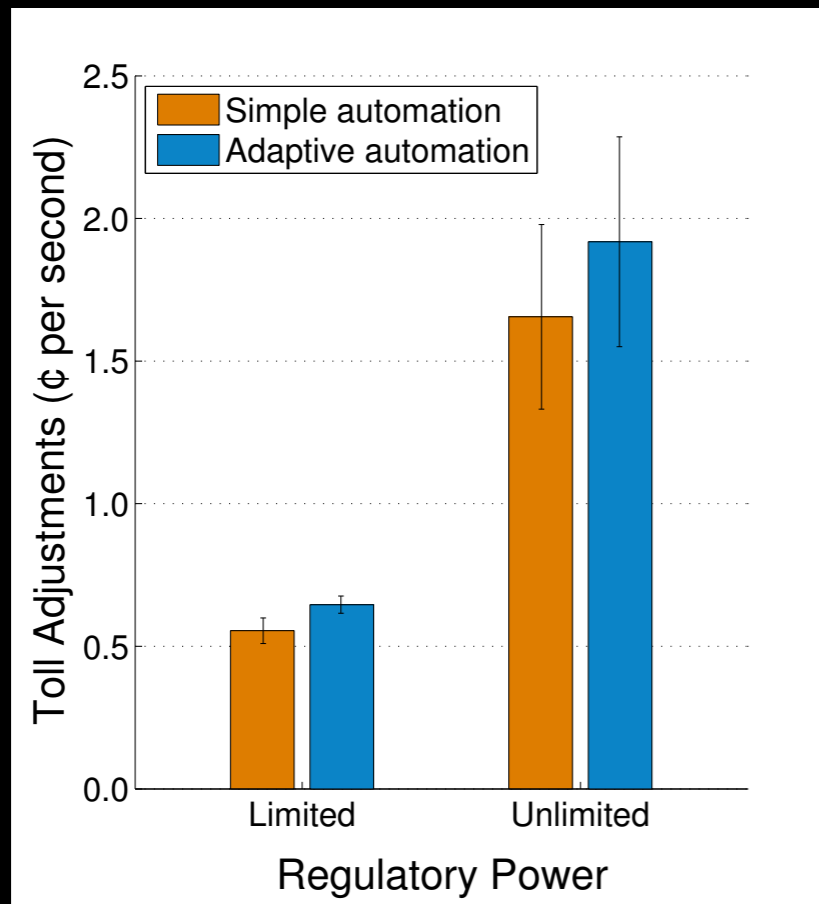
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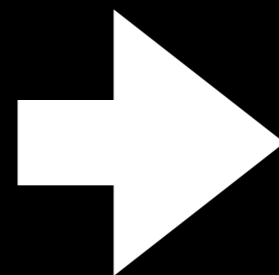
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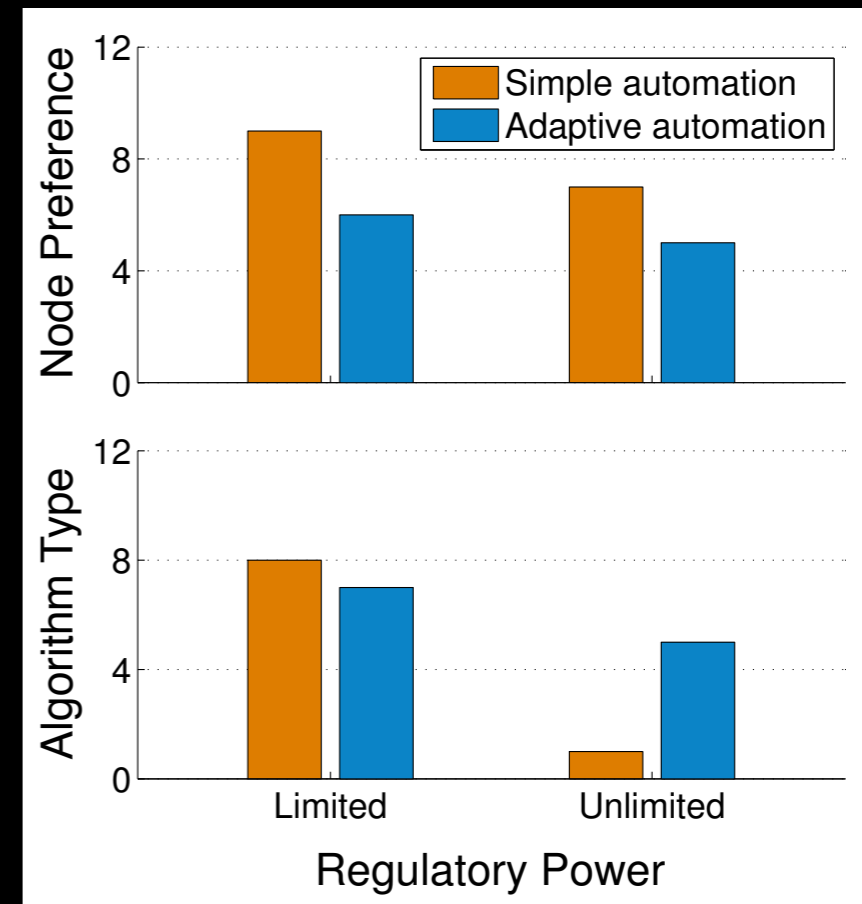
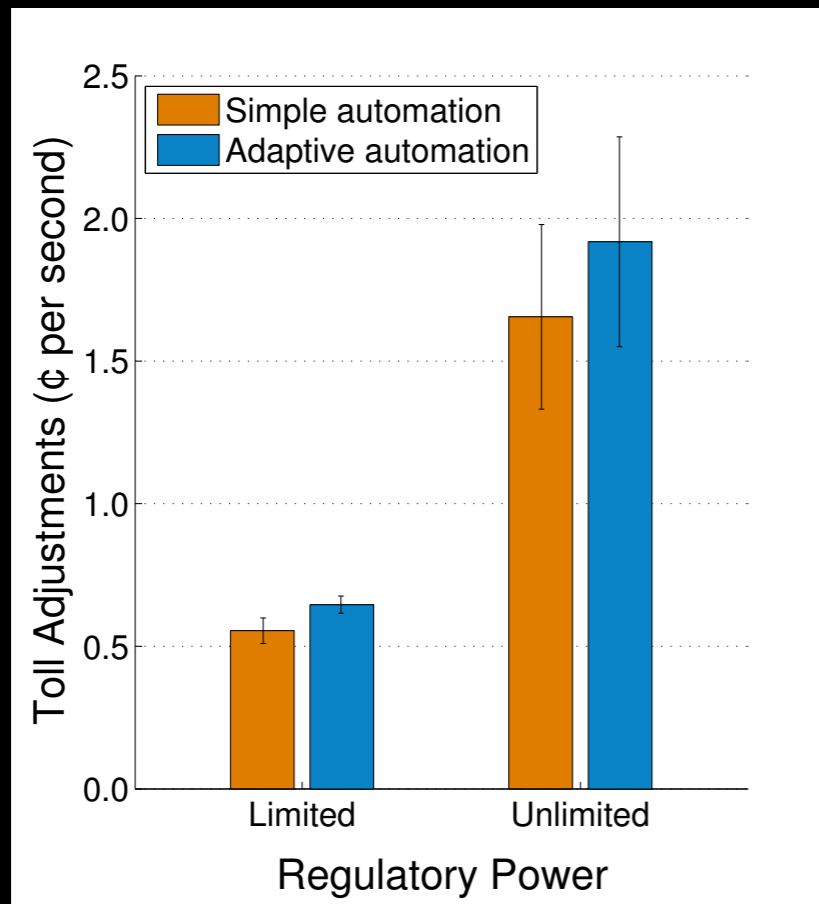


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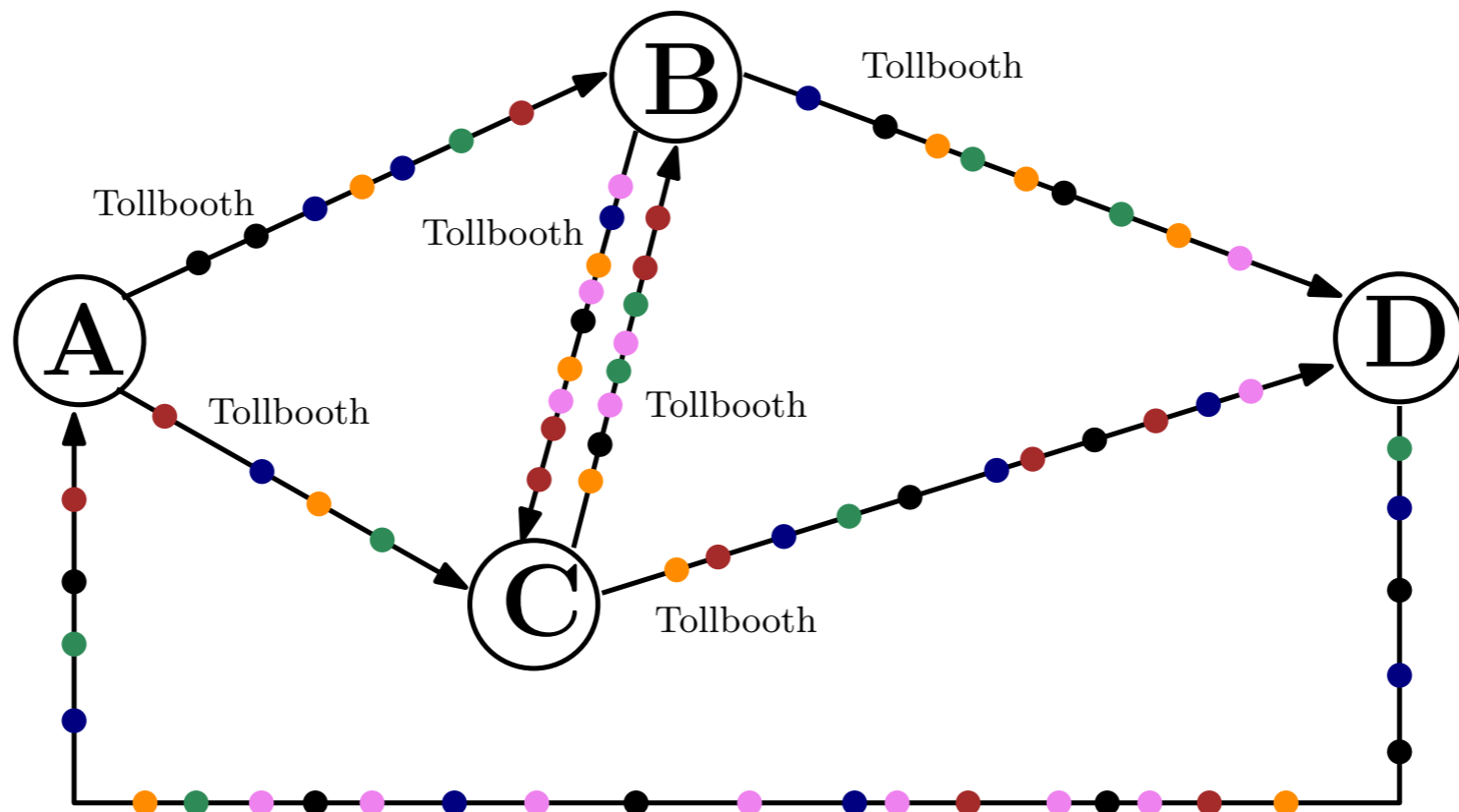
Regulators had poorer  
models of robot  
behavior

# Why Simple-Unlimited?



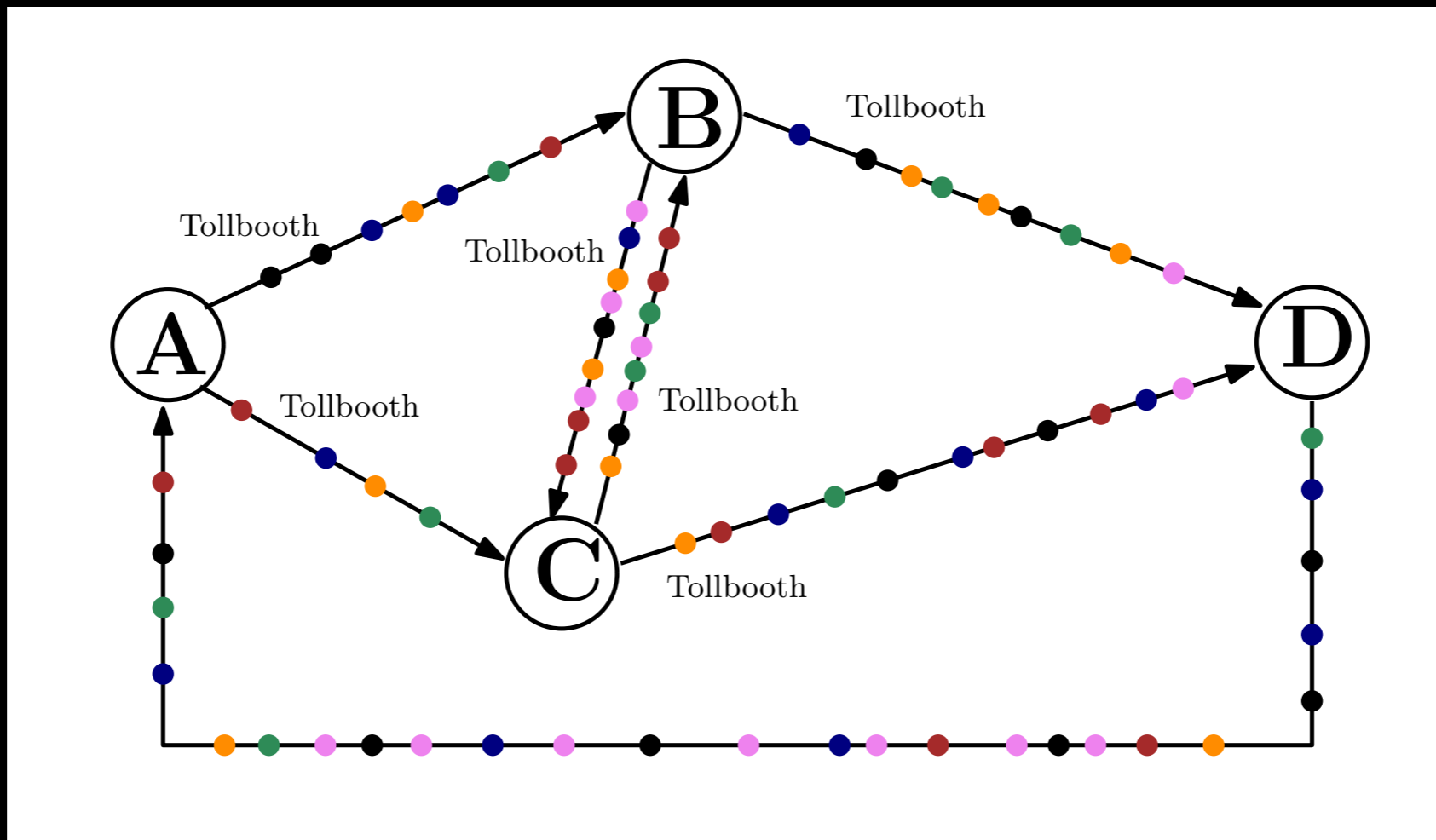
Simple automation was easier to model

# Automated Help



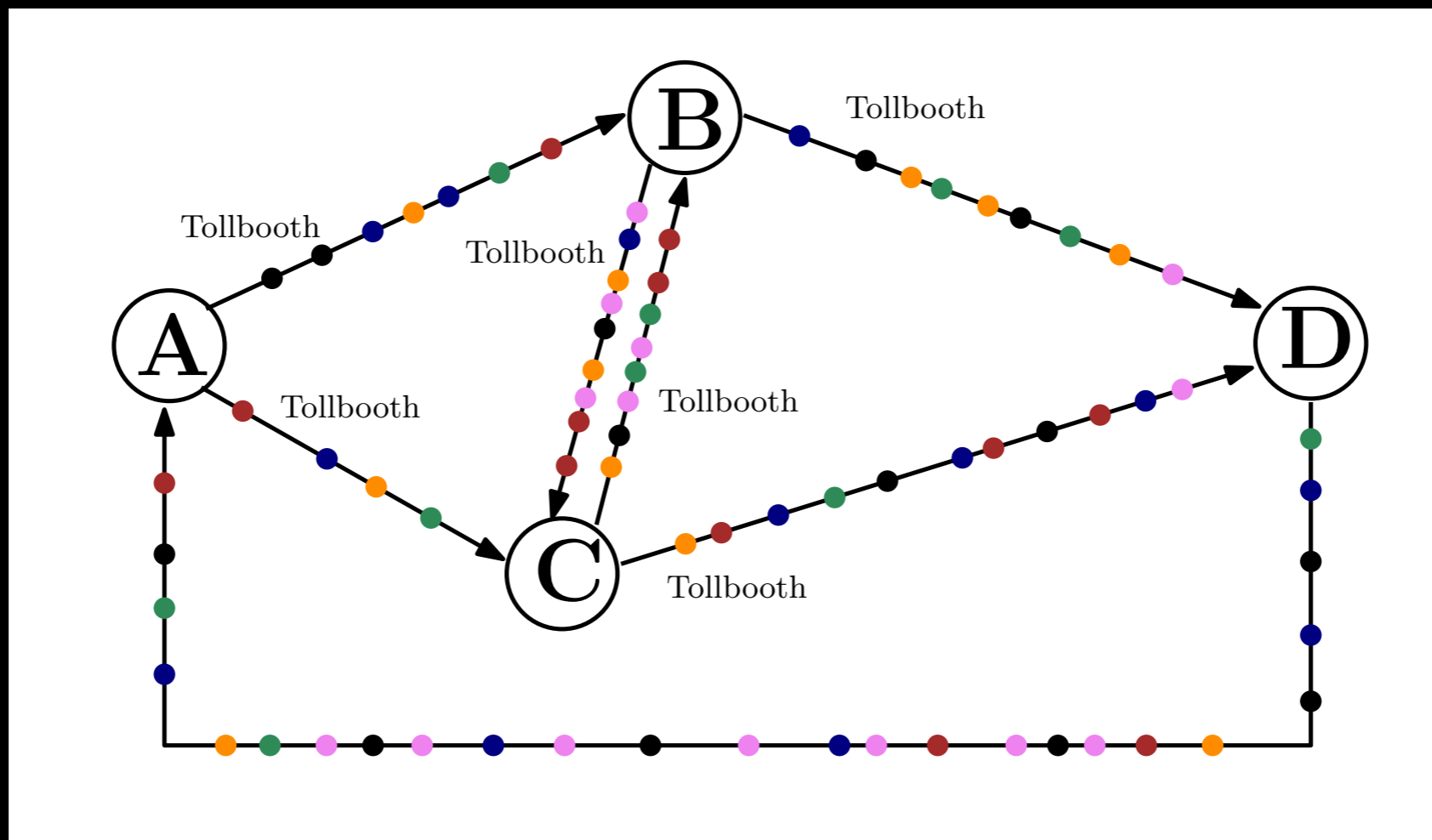
# Automated Help

- Predict when the congestion will occur



# Automated Help

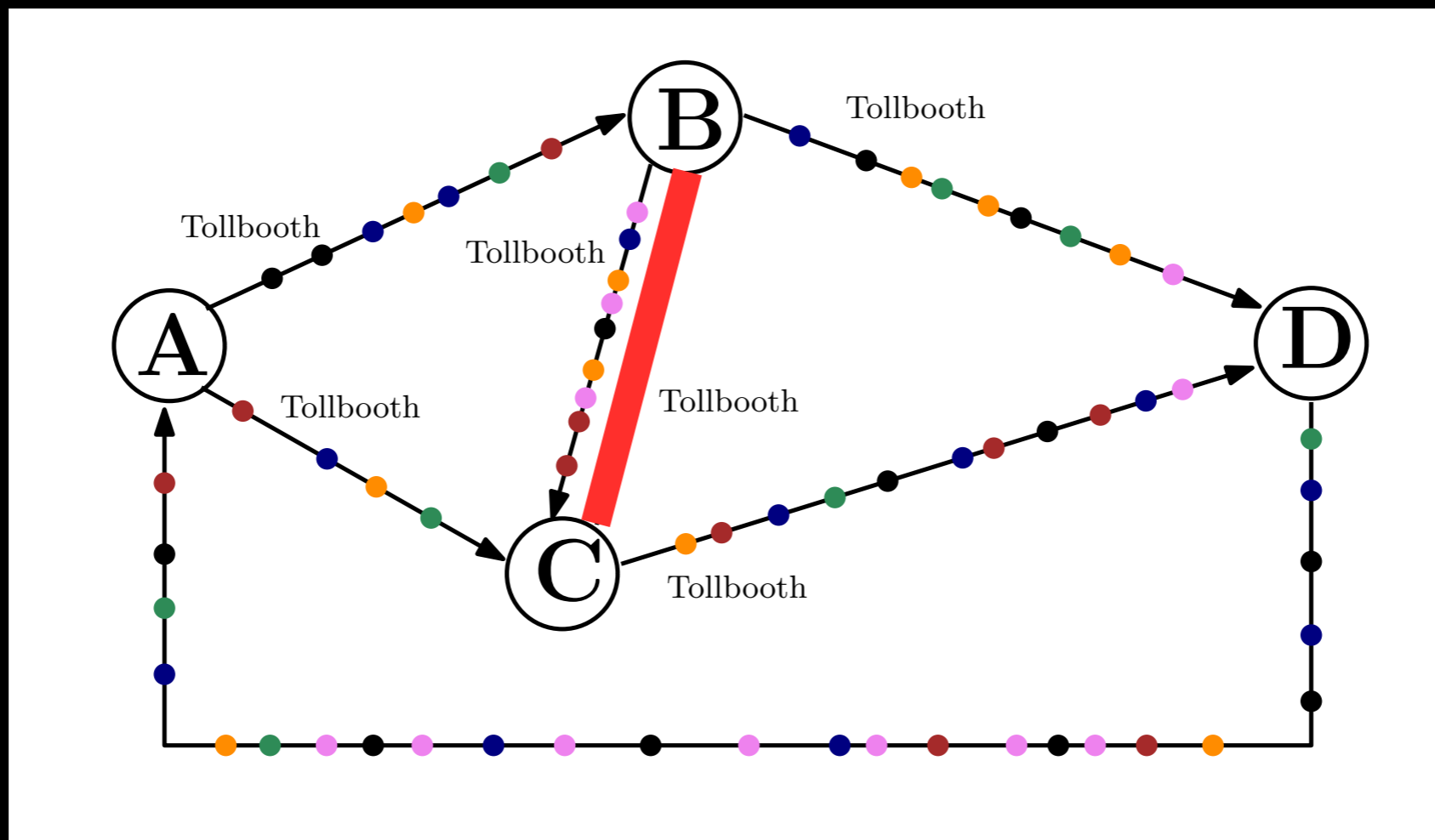
- Predict when the congestion will occur
- Alert the regulator of predicted congestion



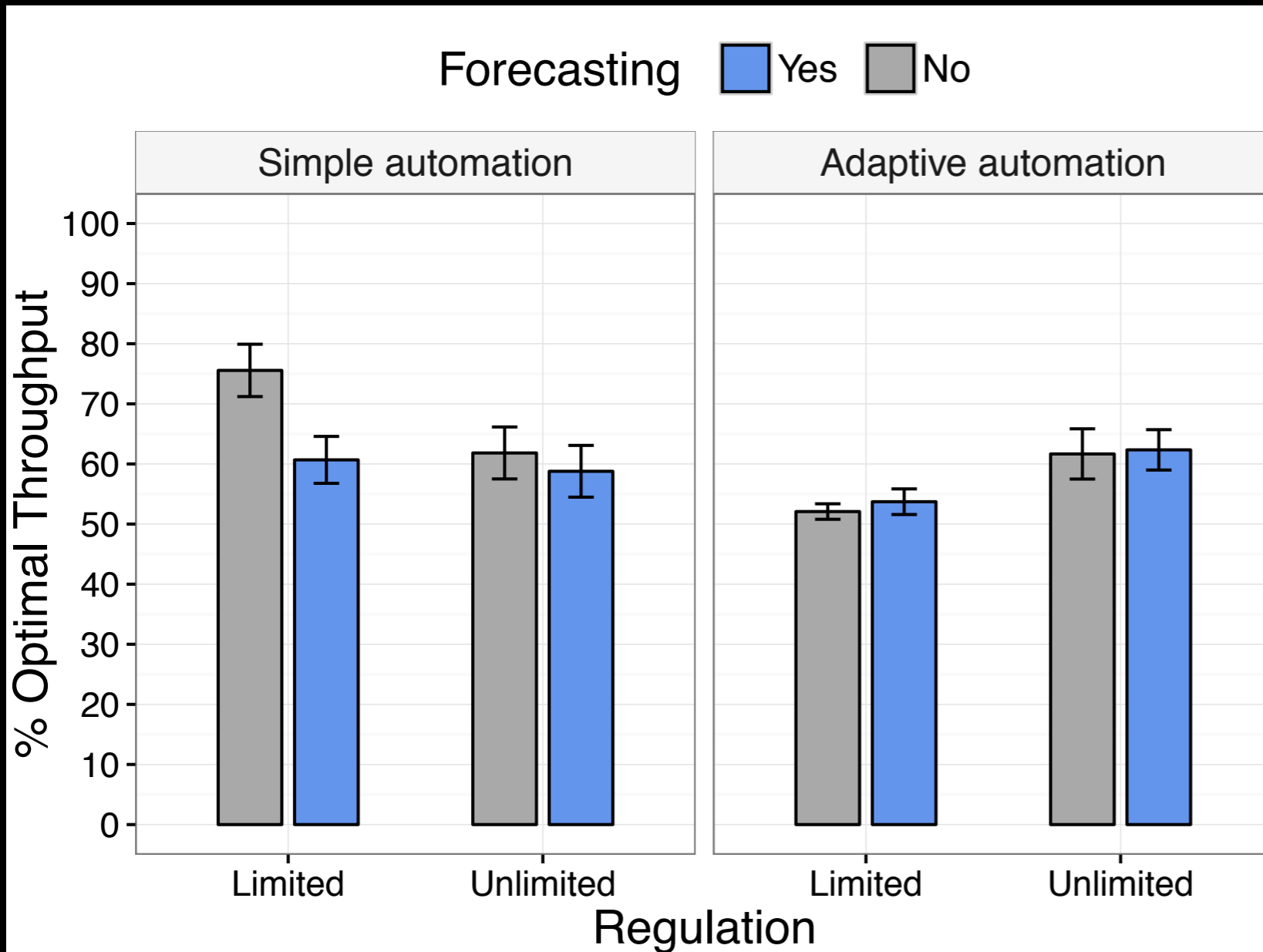


# Automated Help

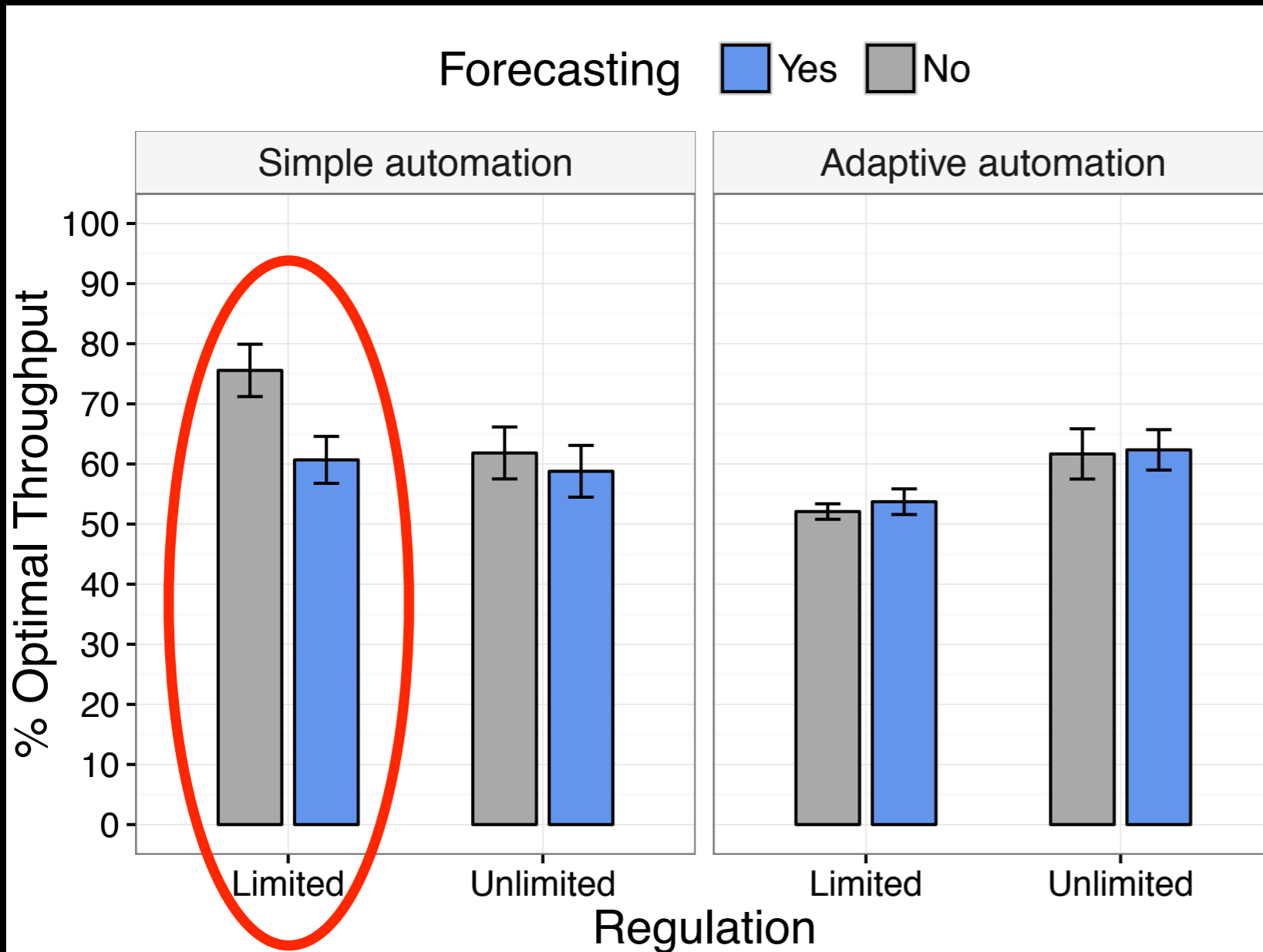
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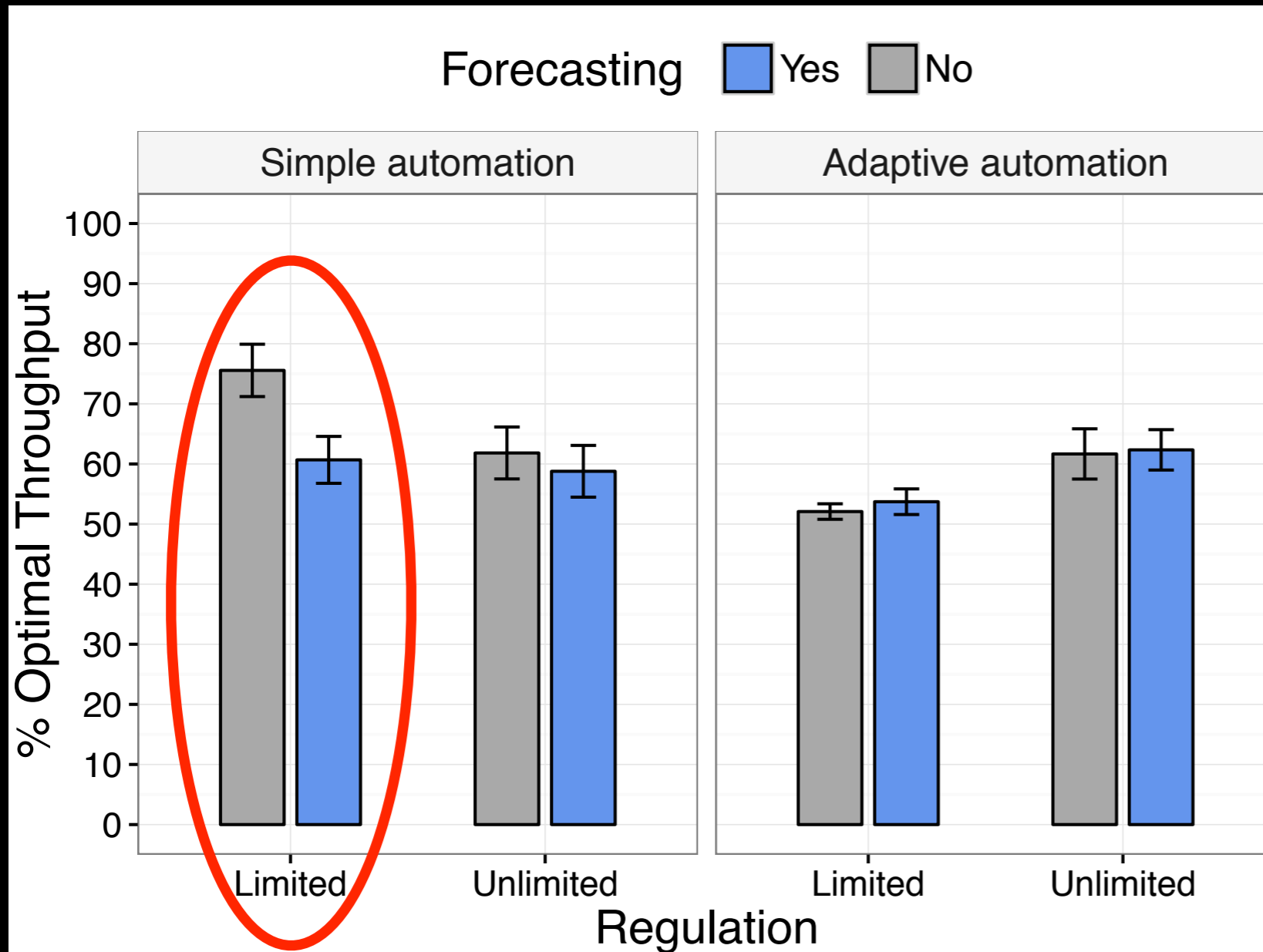
# Outcome



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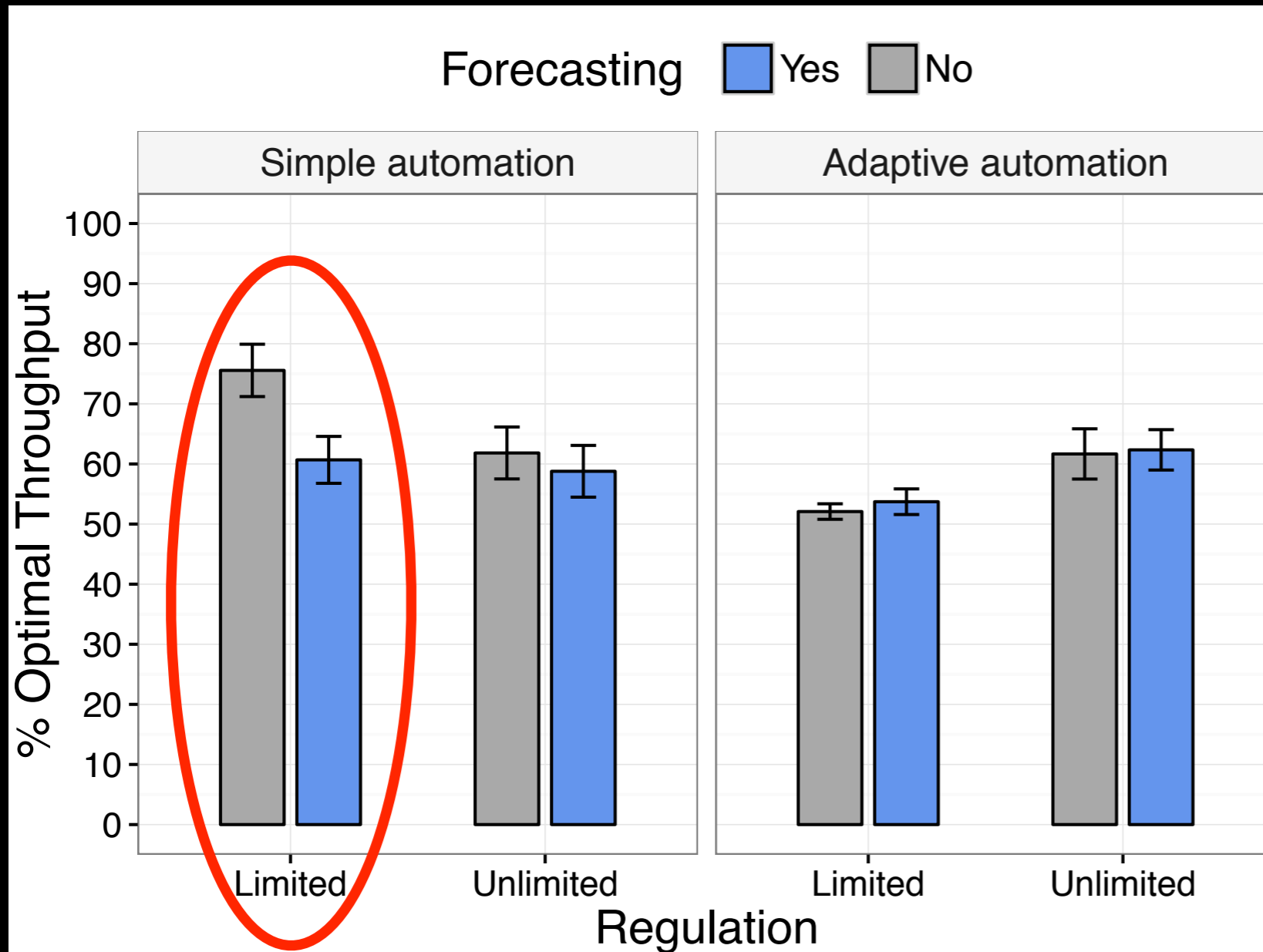


# Outcome



Decision support  
made Simple-Limited  
worse!

# Outcome



Decision support made Simple-Limited worse!

Why? Regulators had a poorer model of the cars.

# Toward a General Theory

## 3 “Forces”:

- Adaptive robots -> Regulator must spend more time modeling
- Adaptive robots -> Regulators need more regulatory power
- More regulator power -> Decreased time modeling robots

# Conclusions and Future Work

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- Data points that suggest less is more



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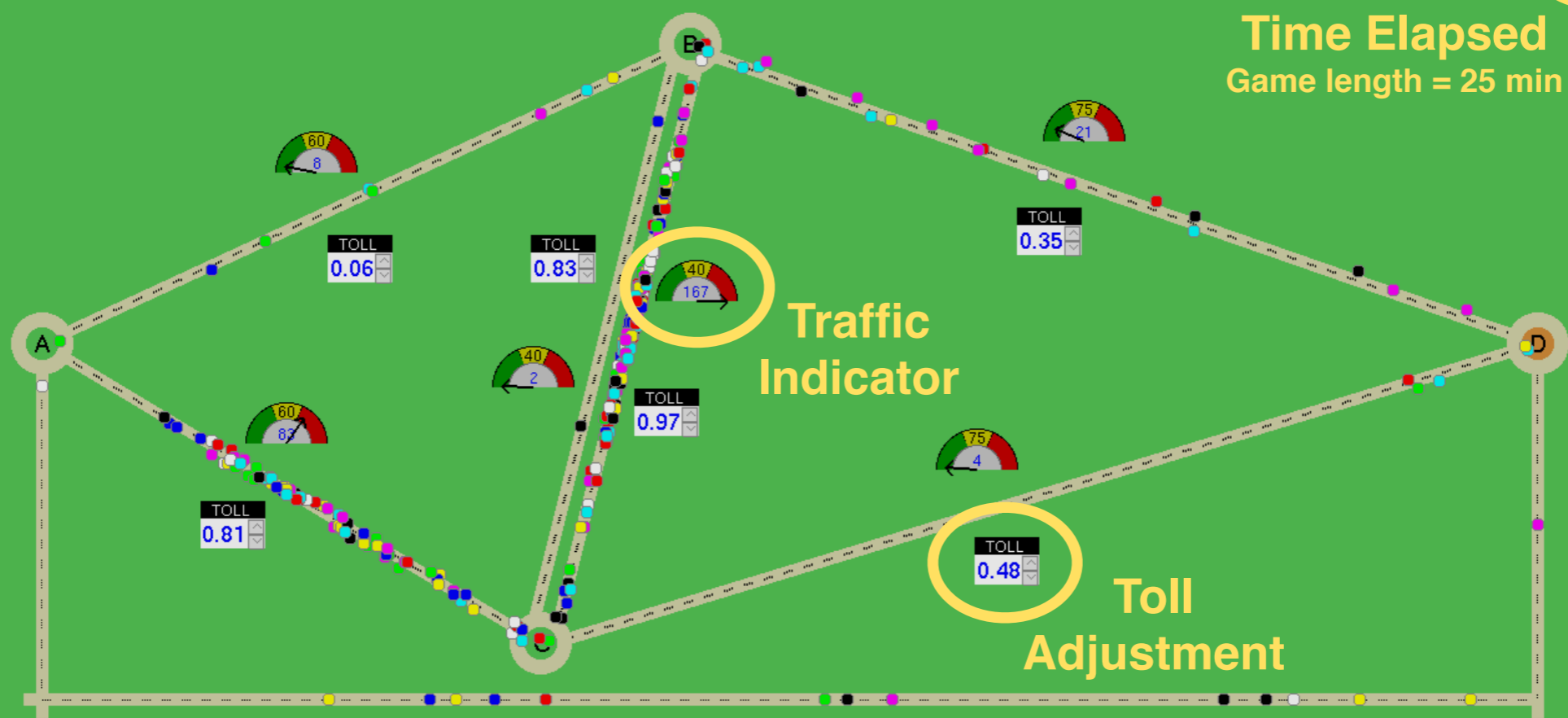
# Conclusions and Future Work

- Data points that suggest less is more
  - **Limited** regulator power with **simple** robots produced the best results
- Just outliers? Or part of a general trend?
- Can we find a way to do more with more?

Extras

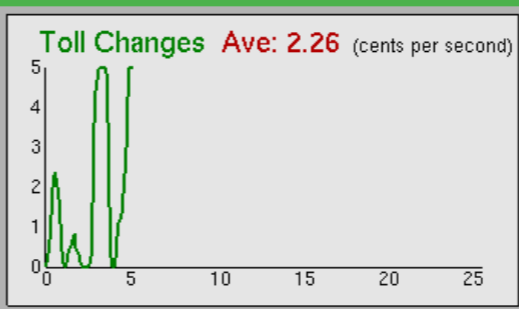
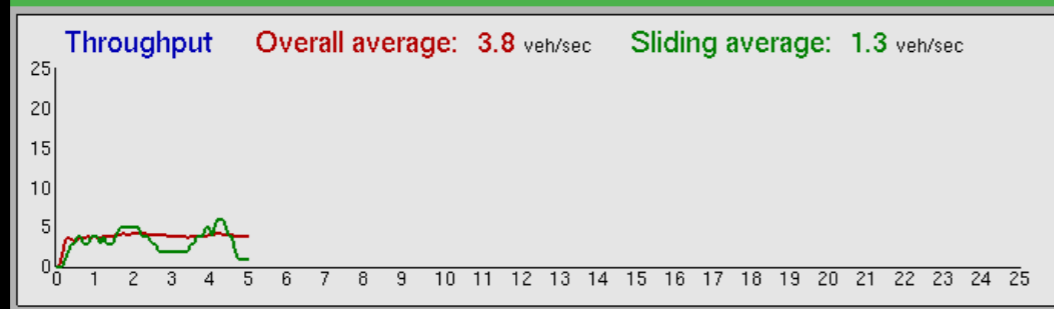
05:04

Time Elapsed  
Game length = 25 min



Traffic Indicator

Toll Adjustment



**High Scores**

Displayed after the game was completed

Your Score: \$ 3.82 / sec