Treating Agent-Interactions in ABMs As Algebraic Structures

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# Introduction

# The nature of the MODULE

To be a module an algebraic structure must contain a primary set that is an additive group, G, satisfying four group axioms: closure, associativity, identity and invertibility. There is an operator ⊕ which takes two elements of the group and yields a third element and its operation satisfies these axioms.

In addition, a module contains a secondary set, R, a ring of coefficients, with a second operation, ⊗, which takes an element of R and an element of G and produces and element of G.

## An Analysis of a Generic ABM Interaction as a Module

### Elements: Following Whitehead (2014), we call the elements of our group *prehensions*. A prehension can be roughly understood as a state of affairs in the world *as seen from a particular point of view*. (In this case the world is the world of our model [see Morgan 2012], but Whitehead views this as a useful metaphysics for the actual world.)

### The operation ⊕, which we will call “prehend”, accepts two prehensions as arguments and produces a third prehension.

#### Axioms:

##### **Closure:** Every prehending involving two prehensions will produce a prehension.

##### **Associativity:** (a ⊕ b) ⊕ c = a ⊕ (b ⊕ c) In a typical agent model, this will mean that we must ensure that, say, a neighborhood can interact with a neighborhood (b ⊕ c), and then with an agent (a ⊕ (b ⊕ c)). Furthermore, this must produce an identical prehension to that produced by an agent interacting with one neighborhood and then another one ((a ⊕ b) ⊕ c).

##### **Identity:** Any prehension prehending the null prehension produces itself.

##### **Invertibility:** For any prehension, there is another prehension that combines with it to produce the null prehension.

### The operation ⊗, which we will call “intensify” (although it may also de-intensify) accepts an element of R and an element of G (a prehension), and produces an element of G.

#### Axioms:

##### a, b ∈ G:

###### (a ⊕ b)x = ax ⊕ bx

###### a(x ⊕ y) = ax ⊕ ay

### Meaning:

#### An agent’s prehension of itself is its view of its own internal state.

#### An agent’s prehension of its environment is its view of its surroundings.

#### But from the point of view of the prehension module, these prehensions are interchangeable.

#### A null prehension could arise, e.g., from the environment when an agent has no neighbors. It could arise internally when an agent has “no opinion” on the relevant parameters, e.g., a color-blind agent in our fashion model.

#### Invertibility may occur, for instance, when an agent has some internal tendency to act in some way (e.g., to move to a new neighborhood or switch fashions) but some force in the environment exactly offsets that tendency (e.g., that “authorities” establish come penalty for so acting).

#### An intensification of a prehension leaves the elements of the prehension in the same internal relationship, but they are scaled up or down relative to other prehensions. This is useful for capturing situations like the gradual dissipation of an attitude, or increasing fanaticism over time.

# The advantages of employing this abstraction

## Why bother?

### We achieve a uniform template for all models as far as how agents interact with their environment.

Programming new models becomes much easier. We have, in fact, been achieving code reductions on the order of 30-40% for models we have converted to the new paradigm.

### We will have taken a huge step towards enabling “fill-in-the-template” style programming of ABMs.

A non-programming user ultimately should be able to build his model by choosing from a palette of possible module operations, setting parameters for each, and chaining them together.

### We open up the possibility of using known properties of modules to identify properties of our ABM.

This has not been achieved yet, but the possibility always remains open.

# a sketch of the usual action pattern

An agent gathers together a prehension of its environment, and then combines that with how it views its own state (its self-prehension) to produce a new prehension. The new prehension may simply be adopted, or it may trigger some further step, such as a movement in space on the part of the agent. And each agent may prehend not only a local slice of the overall environment, but a different sized slice as well.

The combination of very generic processing in treating the prehensions with individual agent flexibility in responding to that outcome allows us to combine some of the best features of older-style simulations with ABMs.

## Some examples:

### Fashion model

The prehension returned from the environment will be a vector representing the mix of fashions being worn in the agent’s neighborhood. The agent will modify her own preferred fashion based on that vector and the sort of agent she is. (Fashion followers will incline toward the prevailing fashion, while trend-setters will move away from it.)

### Financial market model

The prehension returned from the environment will be a vector representing the buy/sell sentiment prevailing around the agent. The agent will modify her own market stance based on that vector and the sort of agent she is. (Chart followers will incline toward the prevailing sentiment, while value investors will move away from it.)

### Schelling’s segregation model

In this model, the agent prehends the color mix of his neighborhood. We normalize the vector we get back, and project it onto the axis representing his own color. His self-prehension represents his minimum percentage “like him” he will tolerate in his neighborhood. If the normalized, projected vector representing the neighborhood Falls below that amount, the agent jumps to a random cell.

However, while the above may be typical, our system allows for the reverse: in some models (e.g., Forest Fire), it may be the environment that adopts the new prehension. Furthermore, environmental prehensions may interact directly with each other as well.

# Implementation details

The following are the main modules implementing this paradigm. They have been written up for maximum readability, in both the comments and especially the code itself. (See Knuth, 1992.)

## prehension.py

1. """
2. prehension.py
3. The way agents interact is through prehensions.
4. entity.py currently has another notion of prehension: that one
5. and this one must be combined in the future.
6. The base implementation of a prehension is as a vector.
7. As of the moment, this is essentially a wrapper around numpy's vector
8. functions. But the reason to do it that way is because other models might
9. want a prehension that is NOT a vector.
10. Sub-class this to instantiate another implementation.
11. """
13. import math
14. import numpy as np
15. # import logging
17. # x and y indices
18. X = 0
19. Y = 1
21. # Set up constants for some common vectors: this will save time and memory.
22. X\_VEC = np.array([1, 0])
23. Y\_VEC = np.array([0, 1])
24. NULL\_VEC = np.array([0, 0])
25. NEUT\_VEC = np.array([.7071068, .7071068])

28. class Prehension:
29. """
30. This duplicates the beginning of this paper!
31. """
32. # we must pre-declare these, then use them, then init them at the bottom
33. #  of the file.
34. X\_PRE = None
35. Y\_PRE = None
36. NULL\_PRE = None
37. NEUT\_PRE = None
39. @classmethod
40. def from\_vector(cls, v):
41. """
42. Convenience method to turn a vector into a prehension.
43. """
44. p = Prehension()
45. p.vector = v
46. return p
48. def \_\_init\_\_(self, x=0, y=0):
49. self.vector = np.array([x, y])
51. def \_\_str\_\_(self):
52. return ("x: %f, y: %f" % (self.vector[X], self.vector[Y]))
54. def prehend(self, other):
55. """
56. In this class, a prehension prehends another prehension
57. through vector addition.
58. other: prehension to prehend
59. """
60. return Prehension.from\_vector(self.vector + other.vector)
62. def intensify(self, a):
63. """
64. Here this is scalar multiplication of a vector.
65. a: scalar to multiply by.
66. """
67. return Prehension.from\_vector(self.vector \* a)
69. def direction(self):
70. """
71. This gets us the orientation of the vector: x, y, or neutral.
72. We use it, for instance, to set an agent's market stance to
73. buy or sell.
74. """
75. if self.vector[X] > self.vector[Y]:
76. return Prehension.X\_PRE
77. elif self.vector[X] < self.vector[Y]:
78. return Prehension.Y\_PRE
79. else:
80. return Prehension.NEUT\_PRE
82. def project(self, x\_or\_y):
83. """
84. Projects the vector onto the x or y axis.
85. Pass in X or Y as declared above.
86. """
87. return self.vector[x\_or\_y]
89. def equals(self, other):
90. """
91. For prehensions of the base type, they are equal
92. when their vetors are equal.
93. """
94. return np.array\_equal(self.vector, other.vector)
96. def reverse(self):
97. """
98. Reverse the vector.
99. """
100. new\_vec = np.array(np.flipud(self.vector))
101. return Prehension.from\_vector(new\_vec)
103. def normalize(self):
104. """
105. Return a normalized prehension.
106. If we get the NULL prehension, just return it.
107. """
108. if self.equals(Prehension.NULL\_PRE):
109. return Prehension.NULL\_PRE
111. return Prehension.from\_vector(self.vector / np.linalg.norm(self.vector))

114. # Now we actually initialize the prehensions we declared above.
115. #  This can't be done earlier, since Prehension was just defined.
116. Prehension.X\_PRE = Prehension.from\_vector(X\_VEC)
117. Prehension.Y\_PRE = Prehension.from\_vector(Y\_VEC)
118. Prehension.NULL\_PRE = Prehension.from\_vector(NULL\_VEC)
119. Prehension.NEUT\_PRE = Prehension.from\_vector(NEUT\_VEC)

122. def stance\_pct\_to\_pre(pct, x\_or\_y):
123. """
124. pct is our % of the way to the y-axis from
125. the x-axis around the unit circle. (If x\_or\_y == Y, it is the opposite.)
126. It will return the x, y coordinates of the point that % of the way.
127. I.e., .5 returns NEUT\_VEC, 0 returns X\_VEC.
128. """
129. if x\_or\_y == Y:
130. pct = 1 - pct
131. if pct == 0:
132. return Prehension.X\_PRE
133. elif pct == .5:
134. return Prehension.NEUT\_PRE
135. elif pct == 1:
136. return Prehension.Y\_PRE
137. else:
138. angle = 90 \* pct
139. x = math.cos(math.radians(angle))
140. y = math.sin(math.radians(angle))
141. return Prehension(x, y)

## prehension\_agent.py

1. """
2. prehension\_agent.py
3. An agent that use Prehensions to understand its environment.
4. """
5. import indra.grid\_agent as ga
6. import indra.prehension as pre

9. class PrehensionAgent(ga.GridAgent):
10. """
11. An agent that use Prehensions to understand its environment.
12. """
13. def \_\_init\_\_(self, name, goal, max\_move=1, max\_detect=1):
14. super().\_\_init\_\_(name, goal, max\_move, max\_detect)
15. self.my\_filter = None
16. self.stance = pre.Prehension()
18. def survey\_env(self):
19. """
20. Look around and see what surrounds us.
21. """
22. super().survey\_env()
23. other\_pre = pre.Prehension()
24. for other in self.neighbor\_iter(view=self.my\_view,
25. filt\_func=self.my\_filter):
26. # accumulate prehensions:
27. other\_pre = other.visible\_stance().prehend(other\_pre)
28. return other\_pre
30. def visible\_stance(self):
31. """
32. By default, just our stance. But we may override this.
33. For instance, perhaps just our direction is visible.
34. """
35. return self.stance
37. def debug\_info(self):
38. """
39. Relevant debugging info.
40. """
41. s = super().debug\_info() + "\nstance: " + str(self.stance)
42. return s

## two\_population\_model.py

## segregation\_model.py

1. import random
2. import indra.prehension as pre
3. import indra.prehension\_agent as pa
4. import indra.grid\_env as grid
6. MOVE = True
7. STAY = False
8. RED = pre.X
9. BLUE = pre.Y
10. RED\_PRE = pre.Prehension.X\_PRE
11. BLUE\_PRE = pre.Prehension.Y\_PRE
12. RED\_AGENT = "RedAgent"
13. BLUE\_AGENT = "BlueAgent"
14. AGENT\_TYPES = {RED: RED\_AGENT, BLUE: BLUE\_AGENT}

17. class SegregationAgent(pa.PrehensionAgent):
18. """
19. An agent that moves location based on its neighbors' types
20. """
21. def \_\_init\_\_(self, name, goal, min\_tol, max\_tol, max\_move=100,
22. max\_detect=1):
23. super().\_\_init\_\_(name, goal, max\_move=max\_move, max\_detect=max\_detect)
24. self.tolerance = random.uniform(max\_tol, min\_tol)
25. self.stance = None
26. self.orientation = None
27. self.visible\_pre = None
29. def eval\_env(self, other\_pre):
30. """
31. Use the results of surveying the env to decide what to do.
32. """
33. # no neighbors, we stay put:
34. if other\_pre.equals(pre.Prehension.NULL\_PRE):
35. return STAY
37. # otherwise, see how we like the hood
38. other\_pre = other\_pre.normalize()
39. other\_projection = other\_pre.project(self.orientation)
40. my\_projection = self.stance.project(self.orientation)
41. if other\_projection < my\_projection:
42. return MOVE
43. else:
44. return STAY
46. def respond\_to\_cond(self, env\_vars=None):
47. """
48. If we don't like the neighborhood, we jump to a random empty cell.
49. """
50. self.move\_to\_empty()
52. def visible\_stance(self):
53. """
54. Our visible stance differs from our internal one.
55. It is just our "color."
56. """
57. return self.visible\_pre

60. class BlueAgent(SegregationAgent):
61. """
62. We set our stance.
63. """
64. def \_\_init\_\_(self, name, goal, min\_tol, max\_tol, max\_move=100,
65. max\_detect=1):
66. super().\_\_init\_\_(name, goal, min\_tol, max\_tol,
67. max\_move=max\_move, max\_detect=max\_detect)
68. self.orientation = BLUE
69. self.visible\_pre = BLUE\_PRE
70. self.stance = pre.stance\_pct\_to\_pre(self.tolerance, BLUE)

73. class RedAgent(SegregationAgent):
74. """
75. We set our stance.
76. """
77. def \_\_init\_\_(self, name, goal, min\_tol, max\_tol, max\_move=100,
78. max\_detect=1):
79. super().\_\_init\_\_(name, goal, min\_tol, max\_tol,
80. max\_move=max\_move, max\_detect=max\_detect)
81. self.orientation = RED
82. self.visible\_pre = RED\_PRE
83. self.stance = pre.stance\_pct\_to\_pre(self.tolerance, RED)

86. class SegregationEnv(grid.GridEnv):
87. """
88. The segregation model environment, mostly concerned with bookkeeping.
89. """
91. def \_\_init\_\_(self, name, width, height, torus=False,
92. model\_nm="Segregation"):
94. super().\_\_init\_\_(name, width, height, torus=False,
95. model\_nm=model\_nm)
96. self.plot\_title = name
97. # setting our colors adds varieties as well!
98. self.set\_var\_color(AGENT\_TYPES[BLUE], 'b')
99. self.set\_var\_color(AGENT\_TYPES[RED], 'r')
100. self.num\_moves = 0
101. self.move\_hist = []
103. def move\_to\_empty(self, agent, grid\_view=None):
104. super().move\_to\_empty(agent, grid\_view)
105. self.num\_moves += 1
107. def census(self, disp=True):
108. """
109. Take a census recording the number of moves.
110. """
111. self.move\_hist.append(self.num\_moves)
112. self.user.tell("Moves per turn: " + str(self.move\_hist))
113. self.num\_moves = 0

## fashion\_model.py

## fmarket\_model.py

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