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Predator-Prey Simulation Using Boids Model

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Collective behavior course research seminar report

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The collective behaviors observed in nature, such as flocking, herding, or schooling, often serve as adaptive strategies that enhance the survival chances of individuals within a group. Understanding these natural behaviors serves as inspiration for designing autonomous agents capable of sophisticated interactions within a simulated environment. Our goal is to simulate prey and predator with different predator tactics (attack center, attack nearest, attack isolated, attacks from various directions, constant bearing hunting), escape maneuvers (split, hourglass, herd, vacuole, flash expansion, fountain) and parameters (perception radius, moving speed, turning speed) in order to conclude how different escape maneuvers affect predator's success.

Collective behavior | Boids | Simulation | Prey-Predator | Escape patterns

Introduction

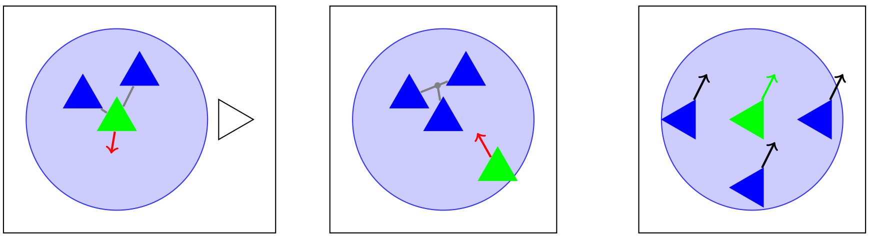
One of the most striking patterns in biology is the formation of animal aggregations. Classically, aggregation has been viewed as an evolutionarily advantageous state, in which members derive the benefits of protection, mate choice, and centralized information, balanced by the costs of limiting resources [2]. We would like to experimentally determine which flocking behaviors help the prey best defend itself against a predator.

The flocking behavior can be simulated in different ways. For example, Heppner and Grenader [3] were modeling birds behavior with stochastic nonlinear differential equations. Oweis, Ganesan, and Cheok [4] took a different approach and modeled birds with a centralized logic (as in the server-client architecture). In 1987, Reynolds [5] proposed a simple algorithm, which was groundbreaking at the time, to model the flocking behavior of birds, herding of sheep, and similar phenomena, known as the Boids (Bird-oid objects) model. In contrast to controlling the interactions of the entire flock, the Boids simulation focuses on dictating the behavior of each individual boid. Despite consisting of a few simple rules, this algorithm produces complex and lifelike behaviors similar to those observed in nature.

Our research is based on a paper by Papadopoulou and others [1], which we will extend with the results of our predator and prey simulation. Although we are not using fuzzy logic to set the direction and speed of our boids, which makes the movement less natural, we have taken some elements for our model from [6]. Specifically, we've set the field of vision for our boids to 300° and implemented occlusion for the predator.

Methods

The Boids model is the foundation of our flocking model. Every object in such a model adheres to the three simple rules as shown in Figure 1.



(a) Collision avoidance (separation). **(b) Cohesion**: gravitate toward the center of the flock. **(c) Alignment**: maintain the same heading and speed.

Figure 1. The basic three rules of the Boids model. We show how the rules apply to a particular boid, marked green, and its neighbors, marked blue. Red arrows indicate the direction in which the observed boid has the tendency to move.

Boids model implementation overview. Each boid B possesses three basic properties: position, velocity, and acceleration. Behavioral attributes include perception radius (r_P), separation radius (r_S), and perception angle (fov). The Euclidean distance, given by $d(p,q)^2 = (p_1 - q_1)^2 + (p_2 - q_2)^2$, is utilized for distance computations.

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Predator-prey interactions is of significant importance in biology and nature itself. The insights gleaned from this research can offer more than a theoretical understanding; they pave the way for the design and optimization of autonomous agents capable of adaptive and context-aware behaviors. The applications range from research in biology to simulations of large amounts of boids found in computer graphics.

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The simulation loop updates boid directions based on three rules: **collision avoidance** (or **separation**), **alignment**, and **cohesion**. The avoidance direction is determined by summing the vector differences between the boid B and its neighbors B_i when their distance is within r_S. The cohesion direction is obtained by averaging the vector differences between the positions of boid B and its neighbors B_i. The alignment direction is computed as the average velocity of neighboring boids B_i, subtracted from the velocity of the boid B, considering neighbors within a perception radius r_P.

The neighbors (all B_i) of a boid B are determined using distance and angle conditions:

$$d(B, B_i)^2 < {r_P}^2 \wedge \text{AngleBetween}(B, B_i) \leq fov \quad [1]$$

Modifying the base Boids model with the **field of vision** is an improvement inspired by [6].

Additionally inspired by [6] is **occlusion**. This effectively disregards boids that remain hidden from the view of a specific boid, as closer boids obstruct their visibility (see Figure 2). Given a list of potential neighboring boids, we must determine which are occluded and in turn take only the nearest (non-occluded) boids as neighbours. This is done by iterating through the list of neighboring boids of boid B and computing the angle between all neighbor pairs (B_i, B_j). If the angle is below a threshold, boids B_i and B_j are considered occluded. Then we just have to determine which neighbor is closer (which one blocks the other). This is done by computing the minimum distance: $min(d(B, B_i), d(B, B_j))$. It is worth noting that we have only added occlusion checks to the predator in our model.

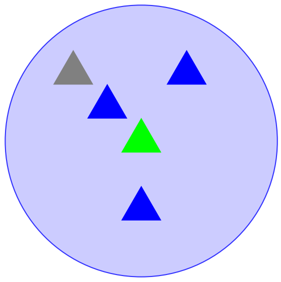


Figure 2. Neighbors (blue) of the observed boid (green). Occluded boid is marked gray.

In order to add even more realism, the **turn speed** of a boid is limited. Whenever the acceleration of a boid is computed, the angle between the acceleration vector and the current heading vector is checked. If it exceeds a threshold, the old heading is rotated by the maximum amount in the given direction and scaled by the magnitude of the acceleration. Therefore boids have a maximum value in which they can turn at each step of the simulation.

Escape maneuvers. Two collective escape patterns that are described in [1] have been implemented: **split** and **herd** as shown in Figure 3.

Figure 3. The basic two escape maneuvers from [1] that we have implemented.

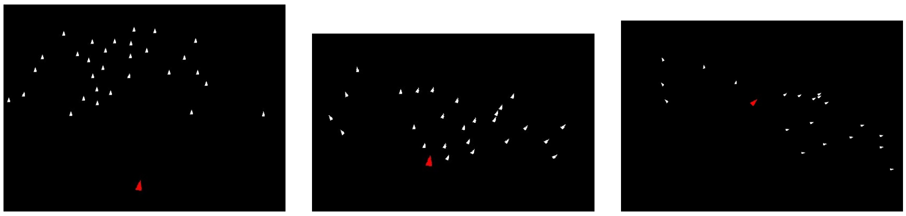
Split is based on predator position. Because of *separation* embedded in our model, prey moves away from the predator once it gets too close.

Herd is based on predator heading. We simply compute the angle between the heading of predator and prey. We take the sign of this angle and rotate the heading of the prey by + or − 90°, depending on sign.

Predators. We have implemented two simple predator attack strategies. In the first one, the predator attacks the center of the flock. This behavior has also been simulated in [6]. In the second strategy, the predator simply attacks a random target.

Results

In Figure 4, we demonstrate the split escape maneuver modeled by our simulation.



(a) Predator chasing a group of boids (step 146).

(b) Start of split pattern (step 233).

(c) Predator caught a prey, split continues (step 261).

Figure 4. A demonstration of the split escape maneuver. Predator and prey positions are shown at various steps of a simulation.

Discussion

This concludes boids implementation with additional realsitic features. The simulation itself was heavily parameterized aswell, making tweakings easiser and more reproducible.

There is still room for improvement in the visualization of the simulation (add traces, add predators target, ...).

The most important aspect which remains is the implementation of different escape manuevers and predator tactics and the comparisons of the latter.

CONTRIBUTIONS. Matija Ojo: Add realistic features, fix escape manuevers, report, Miha Krajnc: Escape manuevers, Janez Kuhar: report, Marko Adžaga: Researching sources and report

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