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ARMA NSGA INTERFACE FOR MILSIM APPLICATIONS

USER'S MANUAL
&
FUNCTION REFERENCE

<dwring@gmail.com>

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SETUP & BASICS

ANIMA is a library for mission designers and has endless applications, but it cannot be dropped in its present state into multiplayer missions. Experienced developers may be able to carefully adapt it by adding conditions in the right places. If anyone does this I would gladly welcome a pull request.

There are many features already built-in to ANIMA that can be used in single player missions with minimal effort. The most benefits are to be had, however, in advanced use of the position finding function, which requires some proficiency with SQF scripting.

I recommend starting with the entire set of scripts and then, later, removing those which are unneeded or unused. But, at the very LEAST, you will need the following folders and files in your mission folder:

```
\include\constants.h
\include\core.h
\include\optimizer.h
\classdef\ObjectRoot.hpp
\core\* <all contents>
\opti\* <all contents>
\init.sqf
```

Init.sqf must contain (in order!):

```
#include <include\core.h>
#include <classdef\ObjectRoot.hpp>
#include <include\optimizer.h>
ClassesInitialized = true;
```

This is sufficient to run the NSGA optimizer and `fnc_find_positions`, but it is highly recommended to use the full included `init.sqf` and all additional folders in order to see some fleshed out examples detailed in later chapters.

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CHAPTER 1 -- INTRODUCTION

ANIMA is a collection of functions and scripts for providing AI groups with terrain/position analysis capabilities that can be used, for example, to dynamically create waypoints with tactical advantage or automatically land helicopters at suitably flat/clear locations.

This release is essentially an open-ended set of scripts for getting AI to do things in abstract terms like "land a helicopter nearby", "find an overlook position with cover and concealment", "ambush nearby roads or intersections", "seek tactical advantage and engage targets"*, or "find a nearby place to unload troops".

These capabilities are implemented with a class system that exposes methods on initialized objects, called like so:

```
[<object>, "<method_name>"(, ...)] call fnc_tell;
```

The heart of ANIMA is the Optimizer class ("opti/Optimizer.hpp"), which is used to set up and control execution of the genetic algorithm. It's not necessary to use it directly, as its operation is encapsulated by `fnc_find_positions` (found in "opti/application_fns.h"). In turn, `fnc_find_positions` is very powerful but requires a lot of configuration and testing for different applications, so its functionality is encapsulated by the `LocationFinder` class, which is then leveraged by the higher-level `Headquarters` class ("classdef/Headquarters.hpp") for mission functionality.

*The order to seek tactical advantage and engage targets is particularly useful when given to several groups of units on each side, on triggers that repeat every couple of minutes and order the attack of all detected units of the other side. Thus multiple groups will continually try to outmaneuver one another and create immersive firefights that can last quite a long time.

CHAPTER 2 -- A FIRST EXAMPLE

As a quick example, we will demonstrate the "land_transports" method of the included "Headquarters" class. The "headquarters" is just a programmatically created Game Logic which stores state information about some units and provides some methods to deploy them.

In the editor, place a crewed transport helicopter Blu_heli_1, and an infantry squad whose leader's init contains the following:

```
{ _x assignAsCargo Blu_heli_1;  
  _x moveInCargo Blu_heli_1;  
} forEach units group this;
```

Create a trigger with activation set to BLUFOR and an area covering the BLUFOR troops, and in its activation field put:

```
_thread = thisList spawn {  
  _waitUntil { not (isNil "ClassesInitialized") };  
  Blu_HQ = ["Headquarters", _this] call fnc_new;  
};
```

*Note that "thisList" above contains the BLUFOR troops, and gets passed (as "_this") to fnc_new as the first parameter used to initialize a new "Headquarters" object.

Finally, place a player unit somewhere else on the map, and provide a radio trigger with its activation set to:

```
_thread = spawn {  
  [Blu_HQ, "land_transports",  
    position player, [Blu_heli_1]] call fnc_tell;  
  [Blu_HQ, "attack_targets", [player], 1] call fnc_tell;  
};
```

Launch the mission and call the radio trigger. After 30-40 seconds the helicopter should start moving and then attempt to land in some nearby field or clearing and let the troops out. The troops should then advance to a position that will ideally give them nearby cover, with intermediate distance and partially occluded line of sight to the player, and carry out a Seek & Destroy waypoint.

Enabling and Disabling Search Markers

If you want to watch the positions on the map as they evolve in real-time, copy the file "classdef/Particle.hpp.MARKERS" over the file "classdef/Particle.hpp". This has an impact on performance and should only be used for testing and development. To disable the markers, copy back "classdef/Particle.hpp.HIDDEN" over "classdef/Particle.hpp".

CHAPTER 3 -- HOW DOES IT WORK?

Let's say we want to find a position to place an invisible helipad near a given location, to give a transport unload waypoint to an AI helicopter. We would do this manually by finding a position that:

- 1) is nearby
- 2) is flat
- 3) doesn't have objects/clutter in the area
- 4) doesn't have easy line-of-sight to hostile areas

ANIMA can do this automatically. It takes a look at some random positions in an area and scores them in all 4 areas: distance, flatness (how much does the Z-coordinate vary in the area surrounding each point?), object clutter (how many objects are within a certain distance?), and line-of-sight (how visible is each point from a predefined set of "enemy" points?). Over a series of generations, the worst positions are discarded and new ones are added relative to the existing ones, and ultimately we are left with a set of points that scored relatively well in all areas. Thus we can programmatically find potential landing zones anywhere on the map at any time during a mission.

The same technique can be used with different objective functions to find positions for other criteria, with the only real limits being the ability of the user to objectively specify what makes a "good" position, and the performance of the algorithm itself, which can be quite slow and requires each application to be optimized as much as possible. In particular it is important to find the simplest and most effective objective functions, and keep the population size and generation count as low as possible while obtaining usable results.

CHAPTER 4 -- FURTHER DETAIL

An NSGA is a "non-dominated sorting genetic algorithm": in essence, this is a technique for evaluating a series of vectors (in this case, positions in the Arma world) across multiple objectives (functions that assign various scores to the positions based on defined criteria). Those positions which have the best scores in any one or more objectives are "cross-bred" to find new, potentially improved candidate positions while the worst positions are dropped. This is repeated for multiple generations until suitably high-scoring positions (across most or all objectives) have been found.

In ANIMA, the initial population of candidate positions is initialized using one of a few different "shape functions" (ring, concentric rings, cross) which return a formation of points around a specified point. This is most often used around a unit or location to begin finding positions nearby. "Cross-bred" positions offset from existing positions based on the distances between other existing positions, meaning that they can get closer or farther away depending on how much the other points are clustered together (ANIMA does this incorporating a method known as "differential evolution").

If the first generation of positions scores best in a small area of the map, subsequent generations will tend to search around that area; however, if the highest scoring positions are spread out then subsequent generations will continue to spread, leap-frogging to new areas in search of better scores. When most of the farther areas are discarded as inferior then the algorithm will start to converge. It's typical that no single best position is ever found, and it's most practical to cut off after a few generations and take the set of points that scored highest in as many objectives as possible. It can be beneficial to include an objective function that scores highest at a certain distance from a unit or location, thus promoting the algorithm to converge at that distance.

CHAPTER 5 -- USING CLASSES

ANIMA makes extensive use of a custom class system for object-oriented method dispatch on game objects. As a hypothetical example, let's assume the existence of a "Dictionary" class with methods to set values, get values, list all stored keys, and retrieve all stored [key, value] pairs. We can initialize a Game Logic in the editor as a Dictionary instance like so:

```
_thread = this spawn {  
  _waitUntil {not isNil "ClassesInitialized"}; // Required at start!  
  [_this, "Dictionary"] call fnc_instance;  
};
```

Classes can also be instantiated without a preexisting editor object, using `fnc_new`. Each new instance will be created as a Game Logic in a dedicated group called `Group_ClassLogic`. This is done like so:

```
// General form:  
_newObject = ["ObjectClassname"<, parameters, ...>] call fnc_new;  
  
// Dictionary class example (constructor doesn't take params):  
MyDict = ["Dictionary"] call fnc_new;
```

Methods are called by sending the method name as the first parameter after the object to `fnc_tell`:

```
// Add a key, value to the dictionary:  
[MyDict, "set", "test key", "some test data"] call fnc_tell;  
  
// Look up the stored value from a key:  
_v = [MyDict, "get", "test key"] call fnc_tell;  
  
// Get all keys stored in the dictionary:  
_keys = [MyDict, "keys"] call fnc_tell;  
  
// Get an alist of all key, value pairs stored using this interface:  
_kvps = [MyDict, "items"] call fnc_tell;
```

Note that we use `fnc_tell` with Arma's `call`, which blocks execution. Never use `call` directly in a trigger or waypoint without wrapping it inside of a new spawned context. This is employed like so:

```
_thread = [] spawn {  
    [<obj>, "<method>", ...] call fnc_tell;  
};
```

In `include\classes.h` there is a series of macros to facilitate the construction of class definition files, as found in `classdef\` in `Dictionary.hpp` and many others. These macros are not required, but provide a slightly cleaner syntax for making a file with several class or method definitions. Without using the macros, it is possible to declare and instantiate classes on-the-fly, while the simulation is running.

CHAPTER 6 -- INCLUDED MODULES

While users are encouraged to envision and implement their own uses of `fnc_find_positions` and the `Optimizer` class, applications can be non-trivial, so I've included some demonstration classes (see Chapter 6 for more information on using the class system).

The HEADQUARTERS Class

The Headquarters can technically be used to control groups of an entire side, but it's mainly intended to manage a subset of groups that are expected to work as a cohesive unit.

Readers should be familiar with this example from Chapter 2 - create a trigger with activation set to BLUFOR and an area covering some BLUFOR troops, and in its activation field put:

```
_thread = thisList spawn {  
    waitUntil { not (isNil "ClassesInitialized") };  
    Blu_HQ = ["Headquarters", _this] call fnc_new;  
};
```

A Headquarters keeps track of infantry groups, vehicles, and loaded transport vehicles. Methods that demonstrate ANIMA functionality include:

approach_targets

```
[Blu_HQ, "approach_targets",  
    <target-list>, <num-transport-to-send>,  
    (<wp-config>), (<nearest-frequency>)] call fnc_tell;
```

Loaded transport vehicles approach a target and unload somewhere out of sight at medium range, intended to maximize nearby cover and occluded lines of sight to the targets. The last two parameters are optional. `Wp-config` can be true, false, or an array of key-value pairs that configure a Waypoint instance. If true (the default), waypoints are full speed/careless; if false, then they are normal speed/aware. `Nearest-frequency` takes a value from 0-1 that gives the percentage chance that only the nearest found waypoint locations will be used. When less than 1, transports are more likely to drive past their target to find a spot to unload.

attack_targets

```
[Blu_HQ, "attack_targets",  
  <target-list>, <num-groups-to-send>,  
  (<wp-config>), (<nearest-frequency>)] call fnc_tell;
```

Groups approach the target(s) and perform a Seek & Destroy waypoint at a nearby location chosen to have cover and occluded lines-of-sight to target(s). Wp-config true is full speed/aware, false is normal/combat.

insurgency_arm

```
[Blu_HQ, "insurgency_arm",  
  <ambush-target>, <ambush-search-radius>, <ambush-type>,  
  <activation-probability>,  
  (<enemies>), (<engage-now?>), (<insurgent-ratio>)] call fnc_tell;
```

This functions alongside the mkcivs module (described later). Finds spots within ambush-search-radius of ambush-target (unit or Game Logic) from which to engage enemies. A percentage of civilians (insurgent-ratio) will go to these positions, join OPFOR, equip weapons and perform Seek & Destroy when the ambush is engaged. Returns an object representing the armed ambush, which can be triggered with the "insurgency_engage" method. The ambush-type is either "intersections", "roads", or "units". "Intersections" and "roads" optimize cover relative to road/intersection positions, while "units" uses the target directly.

land_transports

```
[Blu_HQ, "land_transports",  
  <position>, <helicopters>,  
  (<enemies>), (<radius>), (<n-steps>),  
  (<search-population-size>), (<init-shape>)] call fnc_tell;
```

Sends loaded transport helicopters to land near position, optionally avoiding enemies, where they unload and then wait. Initializes search with given radius, maintains search-population-size candidates during evolution and starts them in pattern given by init-shape. The last five arguments are completely optional and typically not required except in special circumstances.

land_helicopters

```
[Blu_HQ, "land_helicopters",  
  <position>, <helicopters>,  
  (<enemies>), (<radius>), (<n-steps>),  
  (<search-population-size>), (<init-shape>)] call fnc_tell;
```

This method works exactly like land_transports, but doesn't unload any passengers (uses MOVE instead of TR UNLOAD).

Other potentially useful Headquarters methods (non-ANIMA) include:

leaders

```
[Blu_HQ, "leaders", (<named-only?>)] call fnc_tell;
```

Returns an array of all living group leaders tracked by the Headquarters. If named-only is true, then only named units are included.

safety_protocol

```
[Blu_HQ, "safety_protocol", <helicopter>] call fnc_tell;
```

This method simulates an emergency parachute for the player, to be used when riding in a helicopter. If the player ends up outside the vehicle above a certain height AGL (often a result of critical damage), then a parachute will be spawned for the player to have some chance of survival.

watch_for_smoke

```
[Blu_HQ, "watch_for_smoke", <helicopters>, <whose>] call fnc_tell;
```

Monitors <whose> for the throwing of a smoke grenade, which is then watched until stationary. Once it stops moving, the grenade position is passed to the land_helicopters method so they will land nearby.

orbit_position

```
[Blu_HQ, "orbit_position",  
  <position>, <helicopters>, <radius>, <altitude>,  
  (<bearing>), (<counter-clockwise?>),  
  (<n-points>), (<star-pattern?>)] call fnc_tell;
```

Begins a loop in which helicopters are assigned a circular pattern of waypoints on a continually repeating basis, thus orbiting a given position at a given radius/altitude. Several parameters are optional: Bearing represents initial offset, and star-pattern, when true, causes the helicopter to fly to the next waypoint on the opposite side of the circle each time (works well with helicopters that have forward-facing cannons).

orbit_group

```
[Blu_HQ, "orbit_group",  
  <group,-units,-or-position>, <helicopter>, <radius>, <altitude>,  
  (<counter-clockwise?>), (<n-points>), (<star-pattern?>),  
  (<recenter-distance>)] call fnc_tell;
```

This works like orbit_position, but tracks a group instead. Orbit is updated once the group's average position moves more than recenter-distance. Works well after a TR UNLOAD to provide air support.

holding_arc

```
[Blu_HQ, "holding_arc",  
  <focus-group>, <helicopter>,  
  <angle-cw-bound>, <angle-ccw-bound>,  
  <radius-inner>, <radius-outer>, <altitude>,  
  <counter-clockwise?>, <n-points>] call fnc_tell;
```

Employs orbit_group in two directions, to cause helicopter to fly back and forth between bearing angle-cw-bound and angle-ccw-bound, at radius-inner on the inside and radius-outer on the outside. This brings the side guns to bear on a target from a specific direction and can serve after a TR UNLOAD as more effective air support than orbit_group. If the player is in one of the guns then using a large outer-radius can keep the helicopter out of danger when the helicopter turns around and the player faces away.

abort_pattern

```
[Blu_HQ, "abort_pattern", <helicopter>] call fnc_tell;
```

Sets a value on the helicopter to break it out of orbit/holding arc. Please wait after using this for the helicopter to return to idle (use `getVariable` on the helicopter to ensure both "orbitidle" and "arcidle" are either true or undefined - not false - in the helicopter's namespace) before invoking another orbit or holding arc method.

The WAYPOINT Class

While somewhat limited and incomplete, the Waypoint class is utilized as a wrapper around group waypoint creation (which ordinarily uses several different functions) so that a virtual waypoint can be configured with a single call and then reissued multiple times.

An example of how to create and assign such a virtual waypoint in the editor is:

```
_thread = this spawn {
    waitUntil { not (isNil "ClassesInitialized") };
    Blu_Waypoint = [ _this, "Waypoint", "COMBAT", "RED", 15,
                    "Seek & Destroy",
                    "WEDGE", Ø, position _this, "NORMAL",
                    ["true", ""],
                    [Ø, Ø, Ø], "SAD", true] call fnc_instance;
    Blu_Team setCurrentWaypoint
        ([Blu_Waypoint, "to_group", Blu_Team, Ø] call fnc_tell);
};
```

The last statement can be reinvoked if a waypoint is to be reused later.

The MKCIVS Module

This module was created back in the days of Arma 2 as an alternative to BIS's ambient civilians module. Civilian zones are placed as Game Logics in the editor, and initialized as instances of the `CivilianZone` class.

Each civilian zone creates two triggers - one to spawn civilians when the player (or NAMED unit) gets within a certain range, and one to

despawn them again when the tracked units go out of a certain range (the ranges can be set independently). Civilians randomly populate the demarcated area and wander around with a DISMISSED waypoint. When they wander outside a predefined range, their groups are reinitialized, causing them to walk back to where they started and start the DISMISS waypoint all over again. Thus civilians wander around endlessly within a small area.

This module is tightly integrated with the `arm_insurgency` and `engage_insurgency` Headquarters methods. (These behaviors are also available without a Headquarters by using the `KillZone` class). Each civilian has a unique name based on its zone, and civilians can be assigned a callback function for their "Killed" event handlers.

The CIVILIANZONE Class

A `CivilianZone` is initialized by taking a Game Logic from the editor, giving it a unique name (like `civ_zone_1`), and instantiating it with the following init code:

```
_thread = this spawn {
    waitUntil { not (isNil "ClassesInitialized") };
    [_this, "CivilianZone",
        <n-groups>, <max-group-size>, <civ-radius>,
        <spawn-radius>, <despawn-radius>] call fnc_instance;
};
```

CHAPTER 7 -- THE LOCATIONFINDER CLASS

The `LocationFinder` class sets up and makes calls to `fnc_find_positions` to cover a variety of common use cases. Some of them work better than others, but this class should serve as an example of how one might create new applications, or a starting point for further development.

`LocationFinders` do not need to be instantiated from existing objects, it's enough to use `fnc_new`. Use the constructor like so:

```
MyLocFinder = ["LocationFinder"] call fnc_new;
```

The constructor can take one or two additional parameters. The first specifies population size (the default is a very conservative 5, which is fast but not particularly effective - larger populations are slower but much more meticulous in finding good positions). The second is a "shape function".

A shape function is a function of a number n for creating a list of n points ($[x, y, z]$) in a particular 2D shape (normalized so each component is between -1.0 and 1.0 , inclusive). The default shape function, `fnc_make_ring`, is just a circle around the center. Other choices are `fnc_make_square`, `fnc_make_concentric_rings`, `fnc_make_cross`, or `fnc_make_ring_cross` (creates five rings in a cross pattern). These shapes form the initial distribution of search positions.

For example, to create a `LocationFinder` that uses a population size of 15, in five groups of 3 arranged in a "+" pattern, use:

```
MyLocFinder = ["LocationFinder", 15, fnc_ring_cross] call fnc_new;
```

`LocationFinders` may also be configured with their "configure" method:

```
[MyLocFinder, "configure", <list-of-key-value-pairs>] call fnc_tell;
```

It isn't really necessary to use "configure" - if users desire such fine-grained control then I would recommend using `fnc_find_positions` directly - but it can be useful for adjusting center, radius, and other parameters.

Configurable keys of the LocationFinder include:

- populationSize : size of the search population
- shape : this is initialized with [<pop-size>] call <shape-function>;
- radius : How much do we enlarge the shape? (Default: 105)
- objectives : List of Particle objective functions
- assignments : List of key-value pairs to set on each Particle
- center : Position at which to center the Location Finder
- color : Color to use if visible markers are enabled
- postSort : comparator function, true, or false (see Chapter 9).
- allowSingleBin : don't extend search if results are undifferentiated

The LocationFinder instance must often be centered on an initial location prior to operation. This is done with the "set_location" method.

set_location

```
[MyLocFinder, "set_location", <position>] call fnc_tell;
```

Next, LocationFinder instances must be configured with objective functions that define the optimal characteristics of positions to be found. Methods to automatically set these functions for specific goals include:

obj_level_terrain

```
[MyLocFinder, "obj_level_terrain"] call fnc_tell;
```

This method optimizes for positions that have the flattest surrounding area, determined by testing a 5x5 grid of points covering a 12x12m square.

obj_landing_zones

```
[MyLocFinder, "obj_landing_zones"] call fnc_tell;
```

This method optimizes for level terrain that is not water, is ideally not closer than 40m to buildings/trees/large objects, and has unobstructed lines-of-sight within a few meters of the position (using a grid method like the one used to check level terrain).

obj_tactical_approach

```
[MyLocFinder, "obj_tactical_approach", <target-list>] call fnc_tell;
```

This method sets up to assign each optimizer particle with a list of targets, and optimizes for non-water positions that are not in enemy LOS, are ideally about 600m from the targets, have surrounding objects for cover and concealment, and ideally have roads nearby.

obj_tactical_advantage

```
[MyLocFinder, "obj_tactical_advantage",  
  <target-list>, (<avoid-water?>)] call fnc_tell;
```

This method sets up optimization of positions near buildings, large objects, and dense vegetation, about 50 to 75m from targets, with full or partial line of sight to the targets.

obj_sniper_nests

```
[MyLocFinder, "obj_sniper_nests",  
  <target-list>, (<avoid-water?>)] call fnc_tell;
```

This works like obj_tactical_advantage, but ignores buildings and for distance simply optimizes for being at least 300m away.

RUNNING the LocationFinder

In order to get positions from the LocationFinder after initializing and setting it up, we need only call the "run" method with one or two parameters.

```
[MyLocFinder, "run", <n-positions-required>, (<step-target>)]  
  call fnc_tell;
```

The first parameter is how many positions you need. Sometimes the algorithm might only find two or three. If you need more, the algorithm will run again until it has enough. Omit this parameter to get all the positions found in one run.

The second parameter is the target number of steps for the genetic algorithm. This is configurable so if the positions being found are inadequate, increase it. If the positions are fine but taking way too long, decrease it.

CHAPTER 8 -- OBJECTIVE FUNCTIONS

In order for the ANIMA engine to evaluate positions in the world for fitness, it must be supplied with a list of objective functions. Each of these is a function that takes a Particle (Game Logic with a position in 3D space) as its only parameter, and returns a value between 0 and 1 (perhaps counterintuitively, 0 is considered the most fit, and 1 the least). Any conceivable function that meets this definition can be used.

One common technique is to use `setVariable` on the Particles to assign each one with a list of targets (`fnc_find_positions` takes a list of ["<variable>", <assignment>] pairs as one of its parameters and calls `setVariable` on each Particle this way). Then, in the objective functions, use `getVariable` to retrieve the list and perform, for example, LOS or distance checks to the targets.

Included with ANIMA is a function called `fnc_normalizer`, which takes three arguments:

```
[<particle-function>, <min-expected-value>, <max-expected-value>]
```

This is so we can write particle functions that return a range outside of 0-1. The normalizer function returns a version of the original function that does constrain its results to the 0-1 range.

Example: Say we have an objective function that counts the number of targets with LOS to the Particle. It's easiest to just write it to return the count directly, so with 5 targets it would return a value between 0 and 5. Let's call it `fnc_count_los`. To get a function limited to the range we want, we invoke:

```
_fn = [fnc_count_los, 0, 5] call fnc_normalizer;
```

Now `_fn` is a function of one particle that returns a value between 0 and 1 and is suitable for use as an objective function in ANIMA.

There is a problem with our normalized function, though: ANIMA seeks to **minimize** the value of its objective functions. Thus having 5 or more LOS to target in our `fnc_count_los` example would return 1.0, and be considered **least fit**.

We could write our function to invert this, but that's not necessary. Another included function incorporates `fnc_normalizer`, but is more powerful: `fnc_to_cost_function`. This is called like so:

```
_fn = [<maximize?>, <min-expected-value>, <max-expected-value>,
      '[_x]', <original-fn>] call fnc_to_cost_function;
```

The first parameter is a boolean: if set to true, then the returned function is inverted for us. Thus:

```
_fn = [true, 0, 5, '[_x]', fnc_count_los] call fnc_to_cost_function;
```

will give us a function that returns 0 when there are 5 or more lines-of-sight, and returns 1.0 when there are 0.

The unsightly '[_x]' string is the parameters passed to `fnc_count_los`, in string form, where `_x` represents the particle being tested. This allows us to use `fnc_to_cost_function` and change a function that expects a Particle plus additional parameters into a function that only takes a Particle and has the other parameters "baked-in", so to speak.

```
OPT_fnc_distance_from_player =
    [true, 50, 300,
     '[position _x, position player]',
     fnc_euclidean_distance] call fnc_to_cost_function;
```

This example from `opti/objective_fns.h` changes `fnc_euclidean_distance`, a function that takes two positions as arguments, into a new function that takes only a single Particle as a parameter. The new function calls `fnc_euclidean_distance` with the Particle (`_x`)'s position as the first parameter and the player's position as the second parameter, and returns a number from 0 to 1: 0.0 if the distance is 300 or greater, and 1.0 if the distance is 50 or nearer.

With this technique, we can also create basic evaluation functions that take a Particle and a radius, and then turn them into multiple objective functions that operate at different radii.

CHAPTER 9 -- fnc_find_positions

The basis of ANIMA's position finding algorithm is `fnc_find_positions`. This function internally configures the specifics of how the underlying genetic algorithm is executed, while the user provides the required parameters to specify how positions should be evaluated and how much computation will be dedicated to the algorithm.

`fnc_find_positions`

```
[<radius>, <init-array>, <assignments>, <objectives>,  
  <pop-size>, <n-generations>, <number-expected>,  
  (<initial-DE-parameters>), (<seed-form>), (<max-retries>),  
  (<color>), (<post-sort>), (<allow-single-bin>)]  
call fnc_find_positions;
```

<radius>: Specifies the size of the area used for the initial search

<init-array>: List of objects(s) on which the search will be centered

<assignments>: List of key-value pairs denoting variables to be assigned to each Particle prior to evaluation

<objectives>: List of objective functions

<pop-size>: Size of the population of search Particles per generation

<n-generations>: Target number of iterations for the algorithm

<number-expected>: Keep running the algorithm until this many optimal solutions are found

<initial-DE-parameters>: A pair of two values or pairs of values that specify the weight and frequency parameters for the algorithm's differential evolution steps. Pairs are used as start and end values over multiple steps. Weight, between 0 and 2, is how much new candidate particles are perturbed based on the distances between other particles, and frequency, between 0 and 1, is the probability of this perturbation on each component (X, Y, Z). Default is [0.35, 0.8].

<seed-form>: An array of points between $[-1, -1, 0]$ and $[1, 1, 0]$, representing the initial distribution of search Particles. Use a shape function to obtain this.

<max-retries>: If number-expected is not reached in n-generations, then keep running until this number of generations.

<color>: When using visible markers (copy Particle.hpp.MARKERS over Particle.hpp in the opti/ folder), sets the color of markers used for this execution.

<post-sort>: If provided, this can be true, false, or a function that compares two particles and returns whether the first is "superior" by some metric. If true or a function, the resulting positions will be sorted, using either the provided function or a default of the average across all objective scores.

<allow-single-bin>: By default, fnc_find_positions will continue searching beyond the target step count if it hasn't been able to split the population into two or more bins using the non-dominated sorting algorithm. If this is true then search will always conclude at the n-generations.

APPENDIX A -- CLASS REFERENCE

```
Optimizer(pop_size, particle_classname, [particle_color])
.get_position()
.position_offsets()
.set_position()
.uniform_position(position)
.report_position()
.conform_positions(positions)
.conform_units(units)
.fit_terrain()
.do_nothing()
.perturb(n, radius)
.radial_scatter_2d(r_min, r_max)
.displace_shape(points, heading, scale)
.ring_out(radius)
.rings_out(radius, leaves)
.add_objective(objective_fn)
.evaluate_objectives()
.de_candidates(weight, frequency)
.non_dominated_sort()
.sorted_average_distances_3d(subpopulation)
.sorted_average_distances(subpopulation)
.moea_step(candidate_generation_method, candidate_generation_params,
           preevaluation_method,      preevaluation_params,
           bin_creation_method,       bin_creation_params,
           bin_ordering_method,       bin_ordering_params)
.MODE_step(weight, frequency)
```

```
Marker(position, shape, type, size)
.set_alpha(alpha)
.set_brush(brush)
.set_color(color)
.set_direction(direction)
.set_position(position)
.set_shape(shape)
.set_size(size)
.set_text(text)
.set_type(type)
.redraw()
.show()
.hide()
```

```

Particle(color)
.set_position(position)
.get_position(position)
.add_objective(objective_fn)
.evaluate_objectives()
.differential_evolve(other_particle, adjunct_particle,
                    moderator_particle, weight, frequency)

LocationFinder()
.set_location(location)
.obj_level_terrain()
.obj_landing_zones([avoid_list])
.obj_tactical_approach(targets)
.obj_tactical_advantage(targets, [avoid_water?])
.obj_sniper_nests(targets, [avoid_water?])
.run(max_required_positions, target_step_count)

Headquarters([units])
.track(units)
.untrack(units)
.dispatch(n, locations, full_speed?, no_transports?)
.dispatch_transports(n, locations, full_speed?,
nearest_only_frequency)
.radio(msg)
.available()
.available_groups()
.available_transports()
.available_pairs()
.moveable_vehicles([refresh_lists?])
.living_men([refresh_lists?])
.men_from_trigger(trigger_list)
.purge()
.retrack()
.leaders([named_only?])
.regroupify(groups, waypoints)
.approach_targets(targets, n, [limited_speed?, [nearest_frequency]])
.attack_targets(targets, n, [limited_speed?])
.safety_protocol(helicopter)
.insurgency_arm(obj, radius, type, chance, watchlist, [engage?,
[ratio]])
.insurgency_engage(armed_zone, pull_radius, percentage)
.woodland_vests(men)

```

```

.land_transports(position, helicopters, [enemies, [search_radius,
[search_steps, [search_population, [shape_fn]]]])
.land_helicopters(position, helicopters, [enemies, [search_radius,
[search_steps, [search_population, [shape_fn]]]])
.watch_for_smoke(helicopters, whose)
.orbit_position(position, helicopters, radius, altitude, bearing,
                ccw?, n, star?)
.holding_arc(focus_group, helicopter, angle_cw_bound, angle_ccw_bound,
            radius_inner, radius_outer, altitude, ccw?, n,
            [called_recursively?])
.orbit_group(focus_units_or_pos, helicopter, radius, altitude, ccw?,
            n, star?, recenter_distance)
.abort_pattern(helicopter, [called_recursively?])

```

```

UnitGroup()
.center_pos()
.add(unit)
.remove(unit)
.groups()
.reinitialize_groups()
.move()
.sequester()
.desequester()
.timed_patrol()
.add_waypoint()

```

```

CrewUnitGroup()
.assign(unit, role)
.auto_assign(units)
.init_in_place(men)
.board()
.board_instant()
.is_serviceable()

```

```

CivilianZone(group_count, group_size,
zone_radius, spawn_radius, despawn_radius)

```

```

KillZone(type, radius, probability, targets, side)
.arm(population_size, generations)
.engage(pull_radius, probability)

```

APPENDIX B -- FUNCTION REFERENCE

```
fnc_find_positions(<radius>,  
                  <init-array>,  
                  <assignments>,  
                  <objectives>,  
                  <pop-size>,  
                  <n-generations>,  
                  <number-expected>,  
                  [<initial-DE-parameters>],  
                  [<seed-form>],  
                  [<max-retries>],  
                  [<color>])
```

(see Chapter 9 for details)

<initial-DE-parameters> explained:

For initial-DE-parameters, starting with the default [.35, .8] means the differential evolution steps are all run with a differential weight of 0.35 and crossover probability of 0.8. If we use [[2, .35], [.8, .2]] then the first step would use a weight of 2.0 and a probability of 0.8, and the values would decrease linearly each subsequent step to final values of 0.35 and 0.2 on the last step.

FUNCTIONS OF A SINGLE PARTICLE

Parameterized particle functions:

```
fnc_average_distance_to_nearest_terrain_objects(<particle>,  
                                                <nearest-n>,  
                                                <object-classnames>,  
                                                <radius-step>)  
fnc_average_distance_to_nearest_array_members(<particle>,  
                                              <nearest-n>,  
                                              <array>)  
fnc_building_positions_nearby(<particle>, <radius>)  
fnc_buildings_nearby(<particle> <radius>)  
fnc_check_level(<particle>, <grid-step-distance>, <n-grid-steps>)  
fnc_check_LOS_grid(<particle>, <grid-step-distance>,  
                  <n-grid-steps>, <eye-height>)  
fnc_closest_building(<particle>)  
fnc_cover_nearby(<particle>, <radius>)
```

```

fnc_forests_nearby(<particle>, <radius>)
fnc_get_elevation(<particle>)
fnc_get_elevation_target_height(<particle>)
fnc_intersections_nearby(<particle>, <radius>)
fnc_LOS_to_array(<particle>, <array>, <eye-height>, <is-unit-array?>)
fnc_partial_LOS_to_array(<particle>, <array>, <eye-height>,
                        <full-LOS-bias>, <no-LOS-weight>,
                        <is-unit-array?>)
fnc_roads_nearby(<particle>, <radius>)
fnc_surface_is_water(<particle>)
fnc_units_nearby(<particle>, <units>, <distance>)
fnc_vegetation_nearby(<particle>, <radius>)

```

Normalized single-argument objective functions:
 [These are suitable for use in fnc_find_positions]

```

OPT_fnc_above_elevation_target
OPT_fnc_area_LOS_clear
OPT_fnc_area_LOS_not_clear
OPT_fnc_below_elevation_target
OPT_fnc_building_positions_nearby
OPT_fnc_civilians_nearby
OPT_fnc_cover_available
OPT_fnc_cover_unavailable
OPT_fnc_distance_from_player
OPT_fnc_distance_from_roads
OPT_fnc_distance_to_roads
OPT_fnc_distance_from_targets
OPT_fnc_long_distance_from_targets
OPT_fnc_extreme_distance_from_targets
OPT_fnc_distance_to_targets
OPT_fnc_long_distance_to_targets
OPT_fnc_extreme_distance_to_targets
OPT_fnc_forests_clear
OPT_fnc_forests_dense
OPT_fnc_fuel_station_nearby
OPT_fnc_level_surface
OPT_fnc_LOS_to_player_group
OPT_fnc_LOS_to_targets
OPT_fnc_no_LOS_to_player_group
OPT_fnc_no_LOS_to_targets
OPT_fnc_surface_is_water
OPT_fnc_surface_is_not_water

```

OPT_fnc_targets_nearby
OPT_fnc_vegetation_clear
OPT_fnc_vegetation_dense