Contents

1 Introduction

1.1 Introduction

These days, mobile robots have taken place in many fields like industry automation, planetary exploration, entertainment, and construction ..., for their ability to work in extreme environments with high precision and without fatigue[1].Even so, a robot occasionally needs the support of other robots because it is impossible or difficult for them to perform some tasks on their own. For that, a new field has emmerged to deal with these problems, swarm robotics.

Swarm robotics is relatively a new research topic that has gained more attraction in the last few years. It is about studying how a large number of simple robots (a swarm) can collaborate and work together to achieve predefined objectives and tasks that are often difficult or impossible to do for a single robot.[2].

One of the main challgenes that swarm robotics researchs face, is pattern formation. Where the agents (robots) try to form diffrent gemoetric shapes like squeres,trinagles and circles in order to perform a specific task.

We can solve this problem using two different aproches. The first one is a Centrelized method where there exist a centel unit which controles the swarm and give global state access. However, implementing this apporch can be coslty and less robust to faillures. The second aproch is a dicentrilzed one, where each robot have uses local commucintion and have access only to his local state.[3]

Our primary objective in this thesis is to implement an RL algorithm in a system made up of a group of robots in order to form some specific geometric patterns using a decentralized method. Each robot will only have access to its local state and will interact and communicate with its neighbors in order to form the desired shapes.

2 Swarm Robotics

2.1 Swarm Intelligence and Social animal inspiration

Social animal and insects behavior in groups like the bees dancing, wasp's nest-building, ant's collaboration , bird flocking and fish schooling has caught the attention of researchers for their ability to archive complex tasks and working in coordination, which demonstrate some form of swarm intelligence that researchers have taken inspiration from to design and implement swarm robotics systems.[4]

They also report that social insects were able to accomplish thier goals like searching for food, alerting the presence of an enemy, or collaborate to lift heavy objects, without having access to the global state or having a leader to guide them. They were only able to accomplish this by utilizing local interactions and communication, which spread to other members and and prompted group-wide cooperation.[4]

2.2 Swarm robotics and multi robot systems

The early 1980s are when multi robots systems first gained popularity. As the name suggests, multi robot systems introduce the idea of teamwork in order to complete tasks that are challenging or impossible to complete alone by the robots. Seven topics of study have been identified in this feild which includes:

- Biological Inspirations;
- Communication
- Localization, mapping, and exploration;
- Object transport and manipulation;
- Motion coordination;
- Reconfigurable robots.

Swarm robotics is a subfield of multi-robot systems that differs from other multi-robot systems in some ways.[5]

2.3 Swarm robotics

Swarm robotics has no one definition because it is a rapidly developing area and new research is constantly being done in it. But we can take this defintion from a cited paper. "swarm robotics is the study of how large number of relatively simple physically embodied agents can be designed such that a desired collective behavior

emerges from the local interactions among agents and between the agents and the environment."[6].

The main characters of swarm robotis are:

- The robots in the swarm must be autonomous.
- The number of robots in the swarm is large.
- Homogeneity is required in robots. A small number is acceptable if not.
- Robots must be incompetent with regard to the primary task they must complete, otherwise, they will fail or perform poorly.
- Robots are limited to local communication and sensing. It makes sure that coordination is spread, making scalability one of the system's characteristics.[4]

2.4 Swarm robotics properties

Swarm robotics have some properties that describe the system's current condition. Bellow are some of these properties:

Robustness: the ability of the swarm to still function even with the loss of some members of the group or the faillure of some parts of the system.
Scalability: The ability of the system to perform well on smaller or larger group sizes without impacting the performance of the swarm.

Flexibility It is the capability of the swarm to adapt and manage the new changes that occur in the environment

Autonomus: Implys that there is no central authority controlling the behavior of the swarm and each individual is independent of the others.

Local communication The communication among swarm members is local since they don't have access to the swarm's overall state. [7][8]

2.5 Domain of application

In this section, we will list some of the significant fields domains where swarm robotics fits in, and can impact in solving the domain problem.

2.5.1 Tasks that cover a region

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Because of the widespread sensing capabilities that the swarm has, swarm robotics is most suited for tackling problems that cover an area of the space, such monitoring the environment of a lake or surveillance of a specific area.[6][8]

2.5.2 Search and rescue missions

In different types of accident or disasters that happen like earthquakes where the human intervention is difficult, swarm robots can be deployed for these type of missions. examples of such robots are: polyobot, swarm bot and M-TRAN.

2.5.3 Cleaning of oil speals

A swarm of robots can reduce the cost and time in such incidents. an exemple of robots that were deployed to such tasks is: Seaswarm, which was developed by the senseable group at MIT.

2.5.4 Exploration

To investigate Mars, swarm robots like Marsbees have been created. the same holds true for the CoCoRo swarm, which was employed for in-depth underwater investigation.

2.5.5 Agriculture

As they can be used to improve the agriculture and monitor the status if crops.

2.6 Swarm robotics basic tasks and problems

SR problems can be broken down into fundamental tasks that the swarm frequently carries out in an effort to accomplish its objective. this tasks are:aggregation,chain formation,self-assembly,coordinated movement,hole avoidance, foraging and self -deployment[3][4].

2.6.1 Aggregation

Aggregation of the robots is performed in order to accomplish some form or to exchange information. This problem can be easy in a centralized system, but difficult in a decentralized one.

2.6.2 Dispersion

For exploration purposes, sometimes, the swarm must cover a wide range of area without losing the connection between the members, in order to expand the group sensing capabilities.

2.6.3 Pattern formation

Sometimes, the swarm must form some specific patterns like circles,squares or lines in order to lift some objects or traverse some ways corridors.

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