

A Novel Approach to Swarm Control.

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Abstract—Perimeter Compression is a technique where by a void reducing effect can be added to a basic swarming algorithm. The effect is dependant upon perimeter identification and is controlled by applying three weighting factors to the existing swarming formulae. One to the cohesion calculation, one the repulsion calculation, and one to the repulsion field size.

I. INTRODUCTION

When cohesion and repulsion field effects (sometimes referred to as potential fields [2], [9], [12], [22], [23], [17]) are used to create a swarming effect, the stable structures that develop are limited to either straight edges or partial lattices [8]. The maintenance of a well-structured swarm is crucial to effective deployment for applications such as reconnaissance or artificial pollination, where ‘blind spots’ are best eliminated [7], and containment, where the swarm is used to surround an object or region [5]. Over time swarms form regular shapes [19] and perimeters form of partial lattices that may contain so-called *anomalies*, such as concave ‘dents’ or convex ‘peaks’ [10]. These anomalies contribute to the disruption of an otherwise well-structured swarm. The key, therefore, is to ensure that these *anomalies* are dynamically removed from a swarm.

Perimeter compression is a technique that creates a ‘pull’ effect between perimeter agents. It is dependant upon perimeter agent identification as discussed by Eliot et. al. in [8], [9], [10] and discussed in Section IV-A.

The aim of this new algorithm is to reduce the spacing between perimeter-based agents. Figure 1) shows an agent and it fields. S is the sensor field. O_b is the obstacle field. C is the cohesion field and R is the repulsion field. The implementation involves introducing three controlling arrays; k_c which can be used to increase the magnitude of the cohesion vector. k_r which can be used to modify the repulsion vector and R which can be

used to alter the repulsion fields of agents.

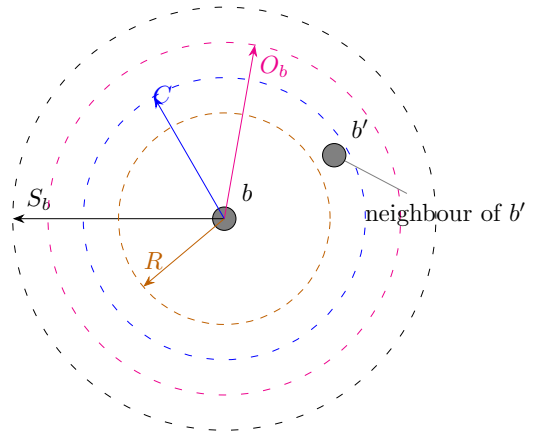


Fig. 1: Agent Fields

II. RELATED WORK

As far back as 1987 swarm theory has adopted the use of field effects/potential fields to coordinate agents [20] and this has continued since then in an attempt to improve the structure of a swarm, coordinate obstacle avoidance, and improve navigation [1], [2], [3], [4], [9], [12], [14], [22], [23]. Improvements to the basic structure of swarms has developed through the likes of a prototype framework for self-healing swarms that was developed by Dai et al. They considered how to manage agent failure in hostile environments [6]. This was similar to work by Vashev and Hinchey, who modelled swarm movement using the ASSL (Autonomic System Specification Language) [26]. This technique was employed by NASA (US National Aeronautics and Space Administration) for use in asteroid belt exploration as part of their ANTS (Autonomous Nano Technology Swarm) project. However, this work is focused towards failure of an agent’s internal systems, rather than on the removal of anomalies in a swarm distribution. This need for formation control is also discussed by Speck and Bucci with respect to the diverse

applications of swarms and the need to control a swarms structure [24].

In the context of swarm structure maintenance, Roach et al. focussed on the effects of sensor failure, and the impact that has on agent distribution [21]. Lee and Chong identified the issue of concave edges within swarms in an attempt to create regular lattice formations [16], and the main focus of their work is the dynamic restructuring of inter-agent formations. Ismail and Timmis demonstrated the use of *bio-inspired* healing using *granuloma formation*, a biological method for encapsulating an antigen [15]. They have also considered the effect failed agents can have on a swarm when traversing a terrain [25].

This paper proposes an alternative approach to agent coordination that can be used to induce a void reduction effect through perimeter compression. This is an extension of the work presented by Eliot et al. [10], Ismail and Timmis [15], [25], and on the work of McLurkin and Demaine on the detection of perimeter types [18]. However, perimeter type identification requires a communications infrastructure to allow the perimeter angle to be calculated. Communications within swarm formations limits swarm sizes and introduces performance problems [11]. The technique employed in this paper does not explicitly require the identification of the perimeter type as it would limit the size of the swarm [10], [16] and is therefore a reduced perimeter detection algorithm to identify *any* perimeter.

III. BASIC SWARMING MODEL

In the Original work by Eliot et. al. the resultant vector of an agent was calculated using Equation 1. Where k_c, k_r, k_d, k_o are weighting factors for the summed vectors associated with each interaction. i.e. v_c, v_r, v_d, v_o for cohesion, repulsion, direction and object avoidance respectively.

$$v(b) = k_r v_c(b) + k_r v_r(b) + k_d v_d(b) + k_o v_o(b) \quad (1)$$

Equation 1 shows the movement vector as a linear combination of a cohesion vector v_c tending to move b towards its neighbours, a repulsion vector v_r tending to move b away from its neighbours, a direction vector v_d tending to move b towards a goal, and a vector v_o tending to steer it away from obstacles. k_c, k_r, \dots are the scalar coefficients of the the linear combination.

This paper does not consider goals or obstacles so we assume $k_d = k_o = 0$ and omit the third and fourth terms.

A. Cohesion

The cohesion component is calculated based on the proximity of neighbours. Where $n_c(b)$ is the set of neighbour agents for b (Eq. 2). The inclusion of an agent from a swarm (S) in by the agent's cohesion field (C).

$$n_c(b) = \{b' \in S : b' \neq b \wedge \|b' - b\| \leq C\} \quad (2)$$

The effect of an agent being within this set is that it will generate a vector that should 'encourage' agents to maintain their proximity. i.e. generate a cohesive swarm. The general weighted (k_c) formula for agents to maintain their proximity is to direct their motion towards the central point of all neighbouring agents as shown in Equation 3. Where $|n_c(b)|$ denotes the cardinality of $n_c(b)$. This formula includes the k_c quotient that allows the cohesion effect to be 'balanced' with respect to other vector influences as described in [8], [9], [10].

$$v_c(b) = \frac{1}{|n_c(b)|} \sum_{b' \in n_c(b)} (b' - b) \quad (3)$$

B. Repulsion

The repulsion component of an agent's movement is calculated from interaction with its neighbours $n_r(b)$ (Eq. 4) in a swarm (S) that are within the agent's (b) repulsion field (R).

$$n_r(b) = \{b' \in S : b \neq b' \wedge |b' - b| \leq R\} \quad (4)$$

The repulsion is then calculated as the average of all the vectors created by the agent (b) to the neighbours (b') (Eg. 5) and its proximity ($\|b' - b\| - R$). Where $|n_r(b)|$ denotes the cardinality of $n_r(b)$.

$$v_r(b) = \frac{1}{|n_r(b)|} \sum_{b' \in n_r(b)} (\|b' - b\| - R) (\widehat{b' - b}) \quad (5)$$

Here, $\widehat{b' - b}$ denotes $b' - b$ normalized to unit length.

IV. NEW INTER-AGENT MODEL

In this paper, we propose that the behaviour of an agent should be modified depending on whether or not it is on a *perimeter*. Figure 2 shows a simple swarm. Perimeter agents are highlighted in **red**. Perimeter-based agents can form part of an inner boundary or an outer boundary. The swarm can

also contain non-perimeter agents which are shown in black.

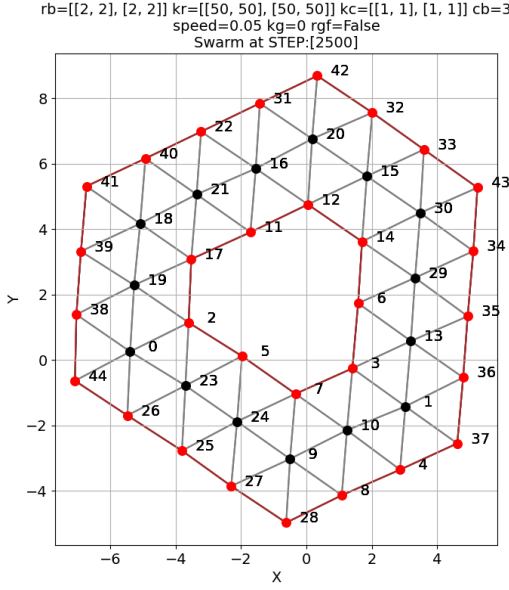


Fig. 2: Outer and inner swarm perimeters.

A. Perimeter detection

is achieved using a cyclic analysis of the agents that surround an agent (Fig. 3). Ghrist et al. discusses a similar technique using sweep angles [13] as does McLurkin et al [18].

When detecting a perimeter it is useful to define an ordering on an agent's cohesion neighbours. We choose to order the cohesion neighbours of an agent b by their *polar angle* with respect to b (Fig. 3).

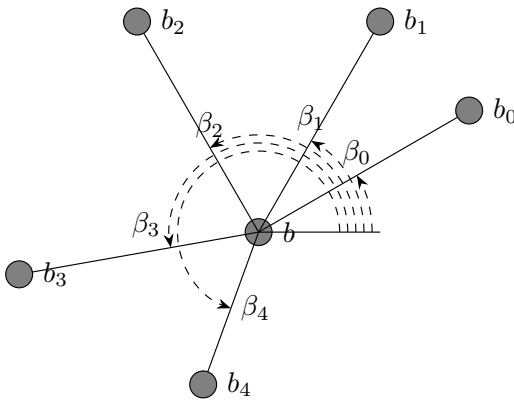


Fig. 3: Agent neighbours

The polar angle with respect to b of b' , $\alpha(b, b')$, is the counterclockwise angle that vector $\vec{bb'} = b' - b$ makes with the positive x axis as shown in Figure 3 and described by Equation 6.

$$\alpha(b, b') = \text{atan2}((b' - b)_y, (b' - b)_x) \quad (6)$$

A partial ordering of agents by polar angle with respect to a specific agent, b , is denoted \leq_{α_b} , and is defined by:

$$b' \leq_{\alpha_b} b'' \iff \alpha(b, b') \leq \alpha(b, b'') \quad (7)$$

We denote by $\langle b_0, b_1, \dots, b_{n-1} \rangle_{\leq_{\alpha_b}}$ a bijection from $\{0, \dots, n-1\} \rightarrow n_c(b)$ that is ordered by polar angle as shown in Figure 4 and more formally in Equation. 8.

$$\forall i, j : 0 \leq i, j, < n \cdot i \leq j \implies b_i \leq_{\alpha_b} b_j \quad (8)$$

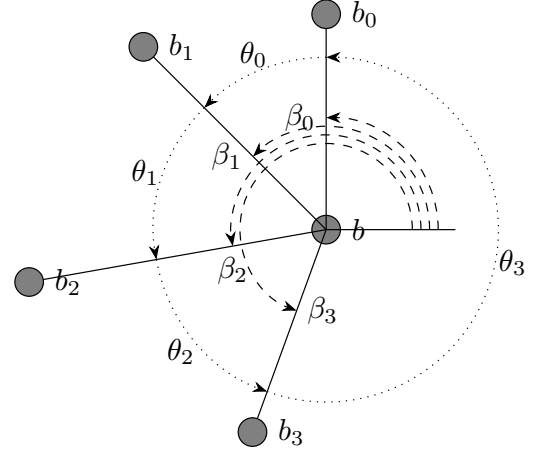


Fig. 4: Agent neighbour angles

An agent b is on a perimeter if it satisfies any one of three conditions:

- 1) consecutive neighbours are not within each other's cohesion field, or
- 2) consecutive neighbours subtend a reflex angle, or
- 3) the agent has too few neighbours.

A function, $\text{prm}(b)$, specifies these conditions formally. Let b be the agent of interest and b', b'' any pair of consecutive neighbours of b in the angle-sorted list $\langle b_0, b_1, \dots, b_{n-1} \rangle_{\leq_{\alpha_b}}$, i.e. $b' = b_i, b'' = b_{(i+1)\%n}$ for some $i \in \{0, \dots, n-1\}$. Then $\text{prm}(b)$ if any one of the following conditions is satisfied:

- 1) $b' \notin n_c(b'')$,
- 2) $\delta > \pi$, where $\delta = \alpha(b, b'') - \alpha(b, b')$ (or $\delta = \alpha(b, b'') - \alpha(b, b') + 2\pi$ if the former is negative), or
- 3) $|n_c(b)| < 3$.

B. R , k_r and k_c

In this section we will discuss the application of the new R , k_r and k_c arrays which are structured as shown below:

| | False | True |
|-------|---------|---------|
| False | $i - i$ | $i - p$ |
| True | $p - i$ | $p - p$ |

Where i represents an internal agent and p is a perimeter agent. These are reflected in the table below with respect to Figure 2:

| | False | True |
|-------|---------|---------|
| False | 39 – 18 | 39 – 41 |
| True | 41 – 18 | 41 – 40 |

The new model requires each agent to modify their inter-agent repulsion and cohesion vectors based upon their perimeter status and each neighbour's perimeter status. The basic perimeter control technique is shown in Equation 9 where the cohesion and repulsion arrays (k_c , k_r , R) are integrated into $v_c(b)$ and $v_r(b)$.

$$v(b) = v_c(b) + v_r(b) \quad (9)$$

1) Cohesion vector:

Cohesion neighbours are identified as described in Equation 2. The cohesion influence is then calculated as shown in Equation 10.

$$v_c(b) = \frac{1}{|n_c(b)|} \sum_{b' \in n_c(b)} k_c[p_b, p_{b'}](b' - b) \quad (10)$$

where $|n_c(b)|$ denotes the cardinality of $n_c(b)$, $p_b = \text{prm}(b)$, $p_{b'} = \text{prm}(b')$, and k_c is a 2x2 boolean-indexed array of constants that determine the weight of a component of the cohesion vector according to whether the interaction between b, b' is between non-perimeter agents, non-perimeter-perimeter, perimeter-non-perimeter, or perimeter-perimeter agents.

2) Repulsion vector:

The set of repellers of b are defined as Equation 11.

$$n_r(b) = \{b' \in S : b \neq b' \wedge b' - b \leq R[p_b, p_{b'}]\} \quad (11)$$

where $p_b = \text{prm}(b)$, $p_{b'} = \text{prm}(b')$, and R is a 2x2 boolean-indexed array of constants that determine the radius of the *repulsion field* for agents in the swarm, according to whether the interaction between b, b' is between non-perimeter agents, non-perimeter-perimeter, perimeter-non-perimeter, or perimeter-perimeter agents.

Now $v_r(b)$ is defined by Equation 12

$$v_r(b) = \frac{1}{\|n_r(b)\|} \sum_{b' \in n_r(b)} k_r[p_b, p_{b'}] \left(1 - \frac{R[p_b, p_{b'}]}{b' - b}\right) (b' - b) \quad (12)$$

where $p_b = \text{prm}(b)$, $p_{b'} = \text{prm}(b')$, and k_r is a 2x2 boolean-indexed array of constants that determine

the weight of a component of the repulsion vector according to whether the interaction between b, b' is between non-perimeter agents, non-perimeter-perimeter, perimeter-non-perimeter, or perimeter-perimeter agents.

C. Gap-filling

In addition to cohesion and repulsion vectors, a *gap-filling* vector can also be used to contribute to agent behaviour. Gap-filling vectors have proven useful in quickly reducing internal voids and in controlling the shape of the external perimeter.

A gap-filling vector for b contributes a motion of b towards the midpoint of a gap identified in the perimeter test for b .

Let $\langle b_0, b_1, \dots, b_{n-1} \rangle_{\leq \alpha_b}$ be the cohesion neighbours of b in polar angle order, and let $b' = b_i$ and $b'' = b_{(i+1) \% n}$ be the first pair of consecutive neighbours that satisfy either condition (1) or condition (2) of the perimeter function $\text{prm}()$, then the gap-filling vector, $v_g(b)$, for agent b is defined in Equation 13.

$$v_g(b) = k_g \left(\frac{b' + b''}{2} - b \right) = k_g \frac{b' - b + b'' - b}{2} \quad (13)$$

If there is no such pair of consecutive neighbours then $v_g(b) = 0$.

k_g is a weighting for the gap-filling vector allowing the combination of it with the other motion vectors (cohesion, repulsion, ...) to be “tuned”.

A stricter alternative to this is to choose the first consecutive neighbour pair b', b'' that satisfy condition (1), ignoring condition (2). This would then exclude any reflex angles that create a ‘gap’. Again, $v_g(b)$ is defined by eq (13) if such a pair exists, or 0 otherwise.

D. Resultant vector

The resultant vector is simply the sum of the cohesion, repulsion and gap-filling vectors as shown in Equation 14 and a resultant swarm segment is shown in Figure 5

$$v(b) = v_c(b) + v_r(b) + v_g(b) \quad (14)$$

metric [9]. The resultant magnitudes generated are shown in figure 7. These states are used as the baseline for the experiments to measure the effects of changing the arrays.

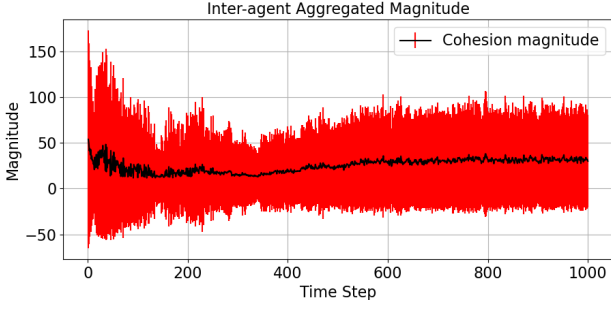


Fig. 7: Baseline swarm in stabilised configuration.

B. Perimeter Compression

$rb=[[2, 2], [2, 1.0]]$ $kr=[[300, 5], [5, 300]]$ $kc=[[1, 1], [1, 10]]$ $cb=3.0$
 $speed=0.05$ $kg=250.0$ $rgf=True$
 Swarm at STEP:[1000]

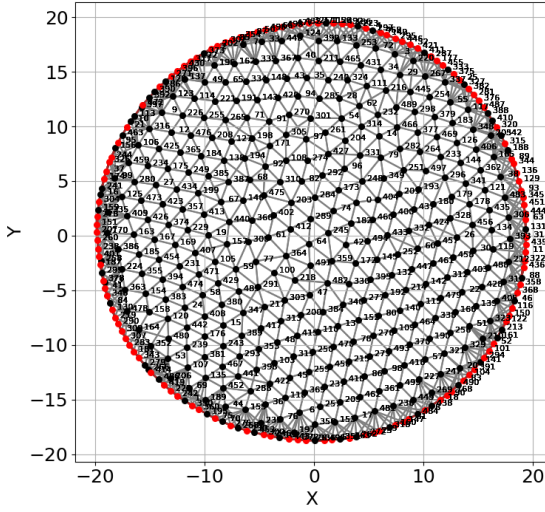


Fig. 8: Tight Perimeter.

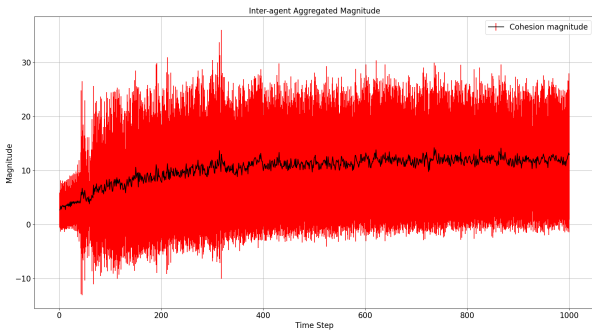


Fig. 9: Tight Perimeter stabilised configuration.

C. Baseline 2

$rb=[[2.0, 2.0], [2.0, 2.0]]$ $kr=[[335.0, 335.0], [335.0, 335.0]]$ $kc=[[1.0, 1.0], [1.0, 1.0]]$ $cb=3$
 $speed=0.05$ $kg=0$ $gap=True$
 Swarm at STEP:[1]

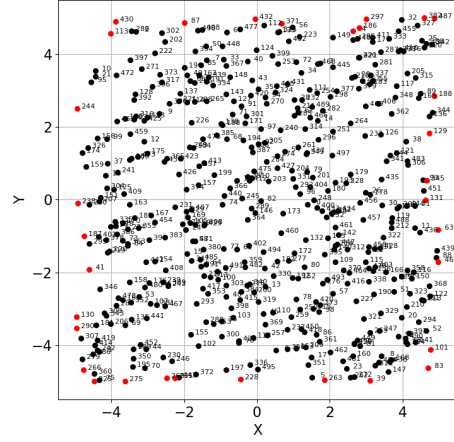


Fig. 10: Baseline 2 start.

$rb=[[2.0, 2.0], [2.0, 2.0]]$ $kr=[[335.0, 335.0], [335.0, 335.0]]$ $kc=[[1.0, 1.0], [1.0, 1.0]]$ $cb=3$
 $speed=0.05$ $kg=0$ $gap=True$
 Swarm at STEP:[1000]

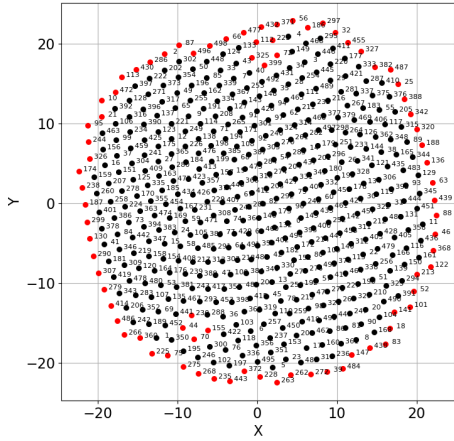


Fig. 11: Baseline 2 end configuration.

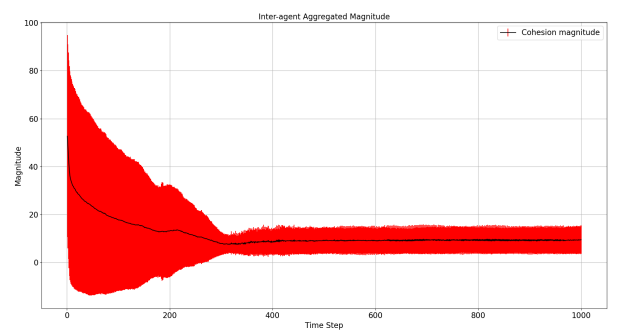


Fig. 12: Baseline 2 stabilised configuration.

D. Perimeter Expansion

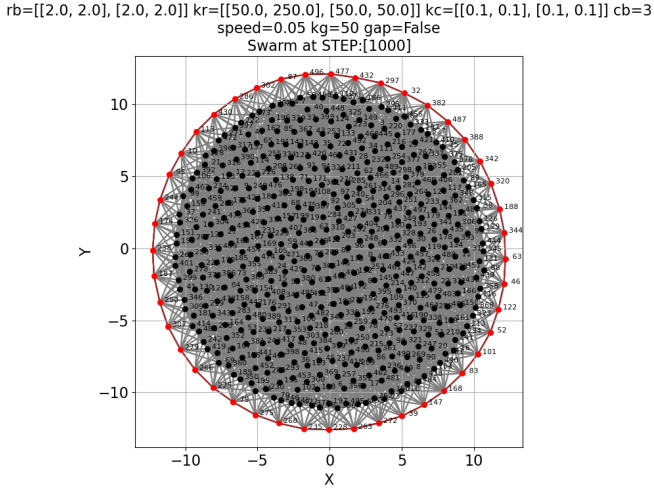


Fig. 13: Perimeter Expanded 1.

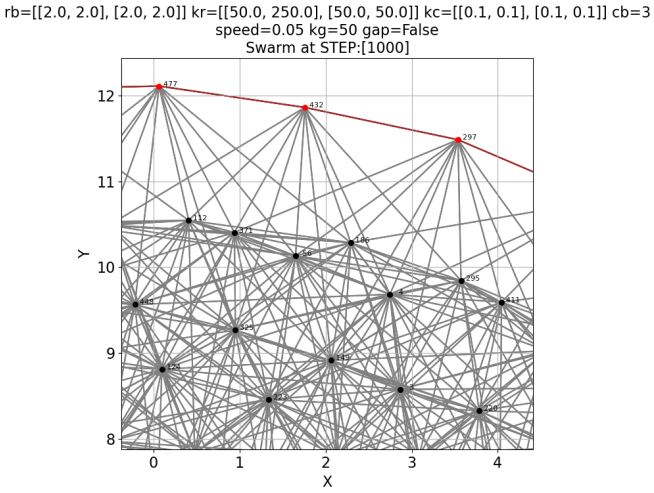


Fig. 14: Perimeter Expanded 2.

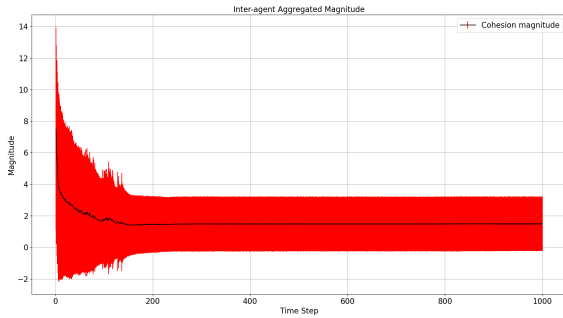


Fig. 15: Baseline 2 stabilised configuration.

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E. Inner compression model

$$p_{kr} = \begin{pmatrix} 1 & x \\ 1 & 1 \end{pmatrix} \quad (18)$$

$$p_{kc} = \begin{pmatrix} 1 & y \\ 1 & 1 \end{pmatrix} \quad (19)$$

1) Inner + Gap compression model:

F. Outer compression model

$$p_{kr} = \begin{pmatrix} 1 & x \\ x & 1 \end{pmatrix} \quad (20)$$

$$p_{kc} = \begin{pmatrix} 1 & y \\ y & 1 \end{pmatrix} \quad (21)$$

1) Outer + Gap compression model:

G. Compression Effects

The compression effect parameters are shown in tables II and III

| Pr/Pc | 10 | 20 | 30 | 40 | 50 |
|-------|--------|--------|--------|--------|--------|
| 0.1 | 0.1/10 | 0.1/20 | 0.1/30 | 0.1/40 | 0.1/50 |
| 0.2 | 0.2/10 | 0.2/20 | 0.2/30 | 0.2/40 | 0.2/50 |
| 0.3 | 0.3/10 | 0.3/20 | 0.3/30 | 0.3/40 | 0.3/50 |
| 0.4 | 0.4/10 | 0.4/20 | 0.4/30 | 0.4/40 | 0.4/50 |
| 0.5 | 0.5/10 | 0.5/20 | 0.5/30 | 0.5/40 | 0.5/50 |
| 0.6 | 0.6/10 | 0.6/20 | 0.6/30 | 0.6/40 | 0.6/50 |
| 0.7 | 0.7/10 | 0.7/20 | 0.7/30 | 0.7/40 | 0.7/50 |
| 0.8 | 0.8/10 | 0.8/20 | 0.8/30 | 0.8/40 | 0.8/50 |
| 0.9 | 0.9/10 | 0.9/20 | 0.9/30 | 0.9/40 | 0.9/50 |

TABLE II: Experiment parameters 1

| Pr/Pc | 60 | 70 | 80 | 90 | 100 |
|-------|--------|--------|--------|--------|---------|
| 0.1 | 0.1/60 | 0.1/70 | 0.1/80 | 0.1/90 | 0.1/100 |
| 0.2 | 0.2/60 | 0.2/70 | 0.2/80 | 0.2/90 | 0.2/100 |
| 0.3 | 0.3/60 | 0.3/70 | 0.3/80 | 0.3/90 | 0.3/100 |
| 0.4 | 0.4/60 | 0.4/70 | 0.4/80 | 0.4/90 | 0.4/100 |
| 0.5 | 0.5/60 | 0.5/70 | 0.5/80 | 0.5/90 | 0.5/100 |
| 0.6 | 0.6/60 | 0.6/70 | 0.6/80 | 0.6/90 | 0.6/100 |
| 0.7 | 0.7/60 | 0.7/70 | 0.7/80 | 0.7/90 | 0.7/100 |
| 0.8 | 0.8/60 | 0.8/70 | 0.8/80 | 0.8/90 | 0.8/100 |
| 0.9 | 0.9/60 | 0.9/70 | 0.9/80 | 0.9/90 | 0.9/100 |

TABLE III: Experiment parameters 2

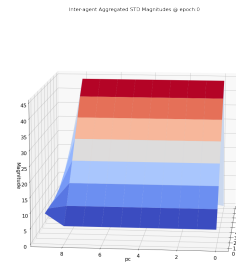


Fig. 16: Experiment Start

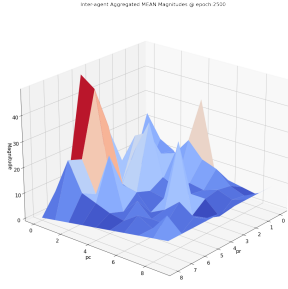


Fig. 17: Experiment Middle

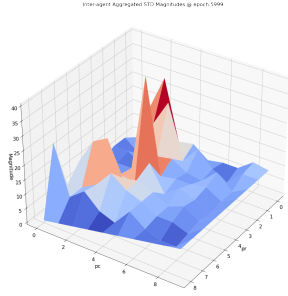


Fig. 18: Experiment End

The first area of comparison is the effect of the algorithms on the number of perimeter agents. The baseline swarm's agents oscillates but remain in a relatively stable state with a constant number of perimeter agents and the internal anomaly persists (Fig. 6). The maximum and minimum number of perimeter agents is shown in table IV.

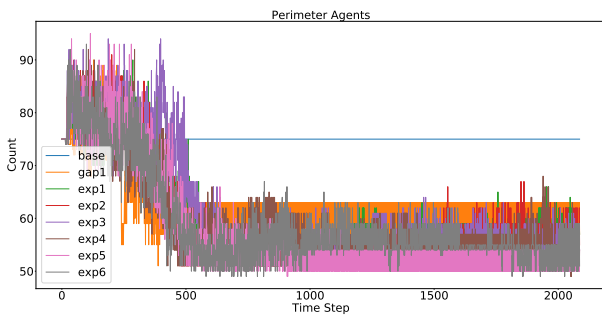


Fig. 19: Perimeter Count of baseline, gap reduction and perimeter compression.

| Comp. | Base | Void | 1 | 2 | 3 | 4 | 5 | 6 |
|-------|------|------|----|----|----|----|----|----|
| Max | 75 | 90 | 90 | 90 | 94 | 92 | 95 | 93 |
| Min | 75 | 51 | 51 | 51 | 51 | 49 | 49 | 49 |
| Mean | 75 | 62 | 59 | 58 | 60 | 59 | 57 | 59 |
| Std | 0 | 6 | 9 | 10 | 10 | 8 | 10 | 8 |

TABLE IV: Perimeter agents

H. Comparison

VI. CONCLUSIONS

From the initial simulations it is possible to show that the technique is able to successfully remove voids and surround an obstacle as shown in the video <https://youtu.be/3eY1vvq0JWo>.

VII. FUTURE WORK

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