

Boids!

Hawk Weisman and Willem Yarbrough

Department of Computer Science
Allegheny College

April 27, 2015

What are Boids?

- ▶ An artificial life simulation [2, 6]
- ▶ 'Bird-oid' flocking behaviour [2, 6]
- ▶ First described by Craig Reynolds in 1987 [6]

Why Boids?

- ▶ Some major appearances:
 - ▶ *Half-Life* (1998)
 - ▶ *Batman Returns* (1992)
- ▶ Other applications:
 - ▶ Swarm optimization [1]
 - ▶ Unmanned vehicle guidance [7, 5]

Our Implementation

- ▶ **Simulation:** Boids in a toroidal 2D space
- ▶ **Haskell** programming language:
 - ▶ A strongly-typed, lazy, purely functional programming language
 - ▶ Why Haskell?
 - ▶ Good for rapid prototyping [3]
 - ▶ Modularity [4]
 - ▶ Prior experience
 - ▶ Explore non-OO ways of representing agents

What is a Boid?

- ▶ A boid consists of:
 - ▶ A position p_i
 - ▶ A velocity vector \vec{v}_i
 - ▶ A sight radius r

What is a Boid?

- ▶ A boid consists of:
 - ▶ A position p_i
 - ▶ A velocity vector \vec{v}_i
 - ▶ A sight radius r
- ▶ In Haskell:

```
type Vector = V2 Float
```

```
type Point  = V2 Float
```

```
type Radius = Float
```

```
data Boid = Boid { position :: !Point  
                  , velocity :: !Vector  
                  , radius   :: !Radius  
                  }
```

```
deriving (Show)
```

Boid Behaviour

- First, we define some types:

```
type Update      = Boid -> Boid
```

```
type Perception = [Boid]
```

```
type Behaviour  = Perception -> Update
```

Boid Behaviour

- First, we define some types:

```
type Update      = Boid -> Boid
type Perception  = [Boid]
type Behaviour    = Perception -> Update
```

- Functions for finding a boid's neighborhood:

```
inCircle :: Point -> Radius -> Point -> Bool
inCircle p_0 r p_i = ((x_i - x)^n + (y_i - y)^n) <= r^n
  where x_i = p_i ^. _x
        y_i = p_i ^. _y
        x   = p_0 ^. _x
        y   = p_0 ^. _y
        n   = 2 :: Integer
```

```
neighborhood :: World -> Boid -> Perception
neighborhood world self =
  filter (inCircle cent rad . position) world
  where cent = position self
        rad  = radius self
```


Separation steering vector

- ▶ Tendency to avoid collisions with other boids

$$\vec{s}_i = - \sum_{\forall b_j \in V_i} (p_i - p_j)$$

Separation steering vector

- Tendency to avoid collisions with other boids

$$\vec{s}_i = - \sum_{\forall b_j \in V_i} (p_i - p_j)$$

- In Haskell:

```
separation :: Boid -> Perception -> Vector
separation self neighbors =
  let p = position self
  in negated $
    sumV $ map (^-^ p) $ positions neighbors
```

Cohesion steering vector

- ▶ Tendency to steer towards the centre of visible boids
- ▶ Calculated in two steps.

Cohesion steering vector

- ▶ Tendency to steer towards the centre of visible boids
- ▶ Calculated in two steps.
- ▶ **Step I:** Find the centre:

$$c_i = \sum_{\forall b_j \in V_i} \frac{p_j}{m}$$

Cohesion steering vector

- ▶ Tendency to steer towards the centre of visible boids
- ▶ Calculated in two steps.
- ▶ **Step I:** Find the centre:

$$c_i = \sum_{\forall b_j \in V_i} \frac{p_j}{m}$$

- ▶ In Haskell:

```
centre :: Perception -> Vector
centre boids =
    let m = fromIntegral $ length boids :: Float
    in sumV (positions boids) ^/ m
```

Cohesion steering vector

- ▶ Tendency to steer towards the centre of visible boids
- ▶ Calculated in two steps.
- ▶ **Step II:** Find the cohesion vector:

$$\vec{k}_i = c_i - p_i$$

Cohesion steering vector

- ▶ Tendency to steer towards the centre of visible boids
- ▶ Calculated in two steps.
- ▶ **Step II:** Find the cohesion vector:

$$\vec{k}_i = c_i - p_i$$

- ▶ In Haskell:

```
cohesion :: Boid -> Perception -> Vector
cohesion self neighbors =
  let p = position self
  in centre neighbors ^~ p
```

Alignment steering vector

- Tendency to match velocity with visible boids

$$\vec{m}_i = \sum_{\forall b_j \in V_i} \frac{\vec{v}_j}{m}$$

Alignment steering vector

- Tendency to match velocity with visible boids

$$\vec{m}_i = \sum_{\forall b_j \in V_i} \frac{\vec{v}_j}{m}$$

- In Haskell:

```
alignment :: Boid -> Perception -> Vector
           -- :: Boid -> [Boid]      -> V2 Float
alignment _ [] = V2 0 0
alignment _ neighbors =
    let m = fromIntegral $ length neighbors :: Float
    in (sumV $ map velocity neighbors) ^/ m
```

Simulating a boid

1. Velocity update

$$\vec{v}_i' = \vec{v}_i + S.\vec{s}_i + K.\vec{k}_i + M.\vec{m}_i$$

Where S , K , and $M \in [0, 1]$

Simulating a boid

1. Velocity update

$$\vec{v}_i' = \vec{v}_i + S.\vec{s}_i + K.\vec{k}_i + M.\vec{m}_i$$

Where S , K , and $M \in [0, 1]$

2. Position update

$$p_i' = p_i + \Delta t \vec{v}_i$$

Simulating a boid

- In Haskell:

```
steer :: Weights -> Behaviour
```

```
steer (s, c, m) neighbors self =
```

```
    let s_i  = s *^ separation self neighbors
```

```
        c_i  = c *^ cohesion self neighbors
```

```
        m_i  = m *^ alignment self neighbors
```

```
        v'   = velocity self ^+^ s_i ^+^ c_i ^+^ m_i
```

```
        p    = position self
```

```
        p'   = p ^+^ v'
```

```
    in self { position = p', velocity = v' }
```

A brief demonstration

References



Zhihua Cui and Zhongzhi Shi.

Boid particle swarm optimisation.

International Journal of Innovative Computing and Applications, 2(2):77–85, 2009.



Christopher Hartman and Bedrich Benes.

Autonomous boids.

Computer Animation and Virtual Worlds, 17(3-4):199–206, 2006.



Paul Hudak and Mark P Jones.

Haskell vs. Ada vs. C++ vs. awk vs.... an experiment in software prototyping productivity.

Contract, 14(92-C):0153, 1994.



John Hughes.

Why functional programming matters.

The Computer Journal, 32(2):98–107, 1989.



Hongkyu Min and Zhidong Wang.

Design and analysis of group escape behavior for distributed autonomous mobile robots.

In Robotics and Automation (ICRA), 2011 IEEE International Conference on, pages 6128–6135. IEEE, 2011.



Craig W Reynolds.

Flocks, herds and schools: A distributed behavioral model.

ACM SIGGRAPH Computer Graphics, 21(4):25–34, 1987.



Martin Saska, Jan Vakula, and Libor Preucil.

Swarms of micro aerial vehicles stabilized under a visual relative localization.

In Robotics and Automation (ICRA), 2014 IEEE International Conference on, pages 3570–3575. IEEE, 2014.