## SWARM INTELLIGENCE

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#### **Introduction 1**

- Swarm intelligence was originally used in the context of cellular robotic systems to describe the selforganization of simple mechanical agents through nearest-neighbor interaction
- It was later extended to include "any attempt to design algorithms or distributed problem-solving devices inspired by the collective behavior of social insect colonies and other animal societies"
- This includes the behaviors of certain ants, honeybees, wasps, cockroaches, beetles, caterpillars, and termites

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#### **Introduction 2**

- Many aspects of the collective activities of social insects, such as ants, are self-organizing
  - Complex group behavior emerges from the interactions of individuals who exhibit simple behaviors by themselves: finding food and building a nest
  - Self-organization come about from interactions based entirely on local information
     IMPORTANT

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#### **Introduction 3**

- Self-organization relies on several components
  - Positive feedback: the recruitment of other insects to forage a food source
  - Negative feedback: limitations on behavior caused by events such as the depletion of a food source
  - Amplification of fluctuations: necessity of random events, such as an ant getting lost but finding a new source of food to exploit
  - Multiple interactions: can be direct (visual, physical, or chemical) or indirect (stigmergy)

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# The Ant System 1

- Work by Dorigo, Minezzo and Colorni (1996)
- A general-purpose heuristic algorithm which can be used to solve different combinatorial optimization problems
  - Versatile
  - Robust
  - A population-based approach
- · The Ant System

# **The Ant System 2**

- One of the problems studied by enthologists was to understand how almost blind animals like ants could manage to establish shortest route paths from their colony to feeding sources and back
- It was found that the medium used to communication information among individuals regarding paths, and used to decide where to go, consists of pheromone trails
- A moving ant lays some pheromone (in varying quantities) on the ground, thus marking the path by a trail of this substance

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## The Ant System 3

- While an isolated ant moves essentially at random, an ant encountering previously laid trail can detect it and decide with high probability to follow it, thus reinforcing the trail with its own pheromone
- The collective behavior that emerges is a form of autocatalytic behavior (positive feedback) where the more the ants following a trail, the more attractive that trail becomes for being followed
  - A higher level of pheromone gives an ant a stronger stimulus and thus a higher probability to choose a certain path
  - An ant chooses the path with the highest pheromone level to use on the return trip, further reinforcing the trail

## **The Ant System 4**

- The Ant System and ant algorithms, derived from the study of real ant colonies
- · Some major differences
  - Artificial ants will have some memory
  - They will not be completely blind
  - They will live in an environment where time is discrete

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## The Ant System 5

- There are n towns; each town has b ants
- Each ant is a simple agent with the following characteristics:
  - It chooses the town to go to with a probability that is a function of the town distance and of the amount of trail present on the connecting edge
  - To force the agent to make legal tours, transitions to already visited towns are disallowed until a tour is completed (this is controlled by a tabu list)
  - When it completes a tour, it lays a substance called trail on each edge visited

    WHEN?

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## The Ant System 6

- The intensity of trail on edge (i,j) at time t is updated based on the evaporation rate of the trail between the time t and t-1, and the quantity of trail substance laid on the edge between t and t-1
- The longer the distance of an edge, the less visible the edge is
- The transition probability from one town to another is then the weighted product of visibility and trail intensity over the sum of all such products
  - Tradeoff between visibility and trail intensity

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# **The Ant System 7**

- The ant-cycle algorithm:
  - At time zero, an initialization phase takes place during which ants are positioned on different towns and initial values for trail intensity are set on edges
  - Thereafter, every ant moves from town to town, choosing the town to move to with a probability (a function of trail intensity and visibility)
  - After n iterations, all ants have completed a tour. For each ant, the value of the distance traversed is recoded. And the shortest path is also computed
  - This process iterates until the tour counter reaches a maximum or until all ants make the same tour (stagnation behavior)

# **Behavior and Applications**

- Insect behavior and applications
  - Looking for food: planning, space planning, constraint satisfaction
  - Arrangement of eggs: data management, sorting, grouping of database information
  - Transportation of food or retrieval of prey: robotics, assembly line design and balancing
  - Prefeeding trails: exploratory
  - Postfeeding trails: recruitment to lead others to the food sources
  - Role allocation: foragers, patrollers, nest maintainers, midden (refuse) workers
  - Older bees may forage for food, while younger bees will stay at the hive and nurse young: task allocation may change when demand dictates, flexible manufacturing process

## **Applications 1**

- Symmetric and Asymmetric Traveling Salesman Problem (TSP)
  - Dorigo M., V. Maniezzo & A. Colorni (1996). The Ant System: Optimization by a Colony of Cooperating Agents. *IEEE Transactions on Systems, Man, and Cybernetics-Part B*, 26(1):29-41
  - Colorni A., M.Dorigo, F.Maffioli, V. Maniezzo, G. Righini, M. Trubian (1996). Heuristics from Nature for Hard Combinatorial Problems. *International Transactions in Operational Research*, 3(1):1-21.
  - Dorigo M. & L.M. Gambardella (1997). Ant Colony System: A Cooperative Learning Approach to the Traveling Salesman Problem. IEEE Transactions on Evolutionary Computation, 1(1):53-66

## **Applications 2**

- The Sequential Ordering Problem
  - Gambardella L. M. and M. Dorigo (1997). HAS-SOP: An Hybrid Ant System for the Sequential Ordering Problem. Tech. Rep. No. IDSIA 97-11, IDSIA, Lugano, Switzerland.
- The Quadratic Assignment Problem
  - Gambardella L. M., E. Taillard and M. Dorigo (1999). Ant Colonies for the Quadratic Assignment Problem. *Journal of* the Operational Research Society, 50:167-176.
  - Maniezzo V. and A. Colorni (1999). The Ant System Applied to the Quadratic Assignment Problem. *IEEE Transactions on Knowledge and Data Engineering*.

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## **Applications 3**

- The Vehicle Routing Problem
  - Bullnheimer B., R.F. Hartl and C. Strauss (1999). An Improved Ant system Algorithm for the Vehicle Routing Problem. Annals of Operations Research (Dawid, Feichtinger and Hartl (eds.): Nonlinear Economic Dynamics and Control, 1999
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## **Applications 4**

- · Scheduling Problems
  - Colorni A., M. Dorigo, V. Maniezzo and M. Trubian (1994).
     Ant system for Job-shop Scheduling. JORBEL Belgian Journal of Operations Research, Statistics and Computer Science, 34(1):39-53.
- The Graph Coloring Problem
  - Costa D. and A. Hertz (1997). Ants Can Colour Graphs. Journal of the Operational Research Society, 48, 295-305.

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# **Applications 5**

- · Partitioning Problems
  - Kuntz P. and D. Snyers (1994). Emergent Colonization and Graph Partitioning. Proceedings of the Third International Conference on Simulation of Adaptive Behavior: From Animals to Animats 3, MIT Press, Cambridge, MA.
  - Kuntz P., P. Layzell and D. Snyers (1997). A Colony of Antlike Agents for Partitioning in VLSI Technology. Proceedings of the Fourth European Conference on Artificial Life, P. Husbands and I. Harvey, (Eds.), 417-424, MIT Press.

# **Applications 6**

- · Telecommunications Networks
  - Schoonderwoerd R., O. Holland, J. Bruten and L. Rothkrantz (1997). Ant-based Load Balancing in Telecommunications Networks. Adaptive Behavior, 5(2):169-207.
  - Di Caro G. and M. Dorigo (1998). Mobile Agents for Adaptive Routing. Proc. of 31st Hawaii Int. Conf. on System, 74-83.
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  - Navarro Varela G. and M.C. Sinclair (1999). Ant Colony Optimisation for Virtual-Wavelength-Path Routing and Wavelength Allocation. Proc. of the Congress on Evolutionary Computation (CEC'99), Washington DC, USA, July 1999.

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### **Applications 7**

- · Parallel Implementations
  - Bullnheimer B., G. Kotsis, C. Strauss (1998). Parallelization Strategies for the Ant System. In: R. De Leone, A. Murli, P. Pardalos, G. Toraldo (eds.), *High Performance Algorithms and Software in Nonlinear Optimization; series: Applied* Optimization, Vol. 24, Kluwer: Dordrecht, 87-100.
- The Single Machine Total Tardiness Problem
  - Bauer, A., B. Bullnheimer, R. F. Hartl, and C. Strauss (1999). An Ant Colony Optimization Approach for the Single Machine Tardiness Problem. Proc. of 1999 Congress on Evolutionary Computation, 1445-1450.

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### **Applications 8**

- The Power Economic Dispatch Problem
  - Song, Y. H., C. S. V. Chou, and Y. Min (1998). Large-Scale Economic Dispatch by Artificial Ant Colony Search Algorithms, Electric Machines and Power Systems, 27(7):87-

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#### More Recent ... 1 (based on Google search)

- Ant-based and swarm-based clustering J Handl... Swarm Intelligence, 2007 Springer ... Given that the focus of our paper is on ant-based and swarm-based clustering, we will disc the use of ant colony optimization (ACO) (Drings) and ... In ACO a number of agents ("arts") independently construct solutions in parallel by steraively augmenting partial so-lations. ... Cleach by 59 Related articles . Print of UNL BL Duter Lall Swarsons
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  Ant colony optimization M Dorigo, M Birattari...... Intelligence Magazine, IEEE, 2006 ieeexplore.ieee.org
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## Swarm 1

- Work by Santa Fe Institute (1994-present)
- The primary goal of the Swarm simulation system is to save researchers from having to deal with all of the programming issues involved in the implementation of concurrent, distributed artificial worlds
- Swarm provides a wide spectrum of generic artificial worlds populated with generic agents, a large library of design and analysis tools, and a kernel to drive the simulation

### Swarm 2

- Swarm 1994
  - Written in pure C
  - Object-oriented in style: Everything in Swarm is an object
  - Objects communicate with other objects by sending them messages
  - All inhabitants of the artificial world (bugs, economic agents, molecules) are objects IMPORTANT
  - Visualization tools part of software

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### Swarm 3

- Swarm 1995
  - For physics, biology, economics, anthropology
  - Object-oriented libraries include Agents, Analysis, I/O, Utilities, Worlds, Design Tools, Visualization, and Spaces
  - Discrete-event, time-stepped schedules
  - Hierarchical organization of agents, and of schedules
  - Parallelism and concurrency: different swarms can be run on different processors
  - Some learning mechanism through reflective roles of nested swarms IMPORTANT

### Swarm 4

- Swarm 1996
  - Multiagent discrete event simulation
  - Heterogeneous swarms
    - · Different animal groups within a swarm
    - · Multi-level modeling
  - Object-oriented for direct instantiation and subclassing
  - Simulation libraries, Swarm support libraries, Model-specific libraries

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#### Swarm 5

• Fast forward to today:

#### Contents

1 Stable release: Swarm 2.2

2 Notes 3 Packaged (binary) distributions (2.2)

3.1 Windows binaries for Objective-C Swarm
3.1.1 MinGW Windows binaries
3.1.2 Cygwin Windows binaries

3.2 Windows binaries for Java Swarm

3.3 GNU/Linux binaries 3.4 MacOS X binaries

3.5 Other platforms 3.6 Binaries of previous versions 4 Swarm source (2.2)

4.1 Compiling Swarm for Windows from source using MinGW
 4.2 Compiling Swarm from source on Ubuntu and Debian Linux
 5 Important Note For Linux/Unix Users on the gcc Compiler

6 Known bugs and fixes
6.1 Error in Averager minimum, maximum values

# Swarm 6

• FAQ (the largest FAQ maintained for Swarm ...)

http://pj.freefaculty.org/SwarmFaq/SwarmOnlineFaq.html

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