

# Swarm Intelligence H-414

Antoine Ligot and David Garzon

IRIDIA-CoDE — Université Libre de Bruxelles, Belgium

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# Pattern Formation

A pattern is an arrangement of objects displaying a mathematical, geometric, or statistic relationship

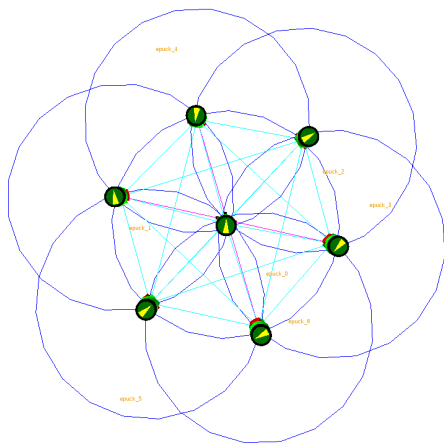


# Pattern Formation with Mobile Robots

Pattern formation is useful for:

- ▶ covering an area with a fixed number of robots
- ▶ achieving a certain network topology
- ▶ flocking (collective motion)

# Pattern Formation with Mobile Robots



## Pattern Formation: idea

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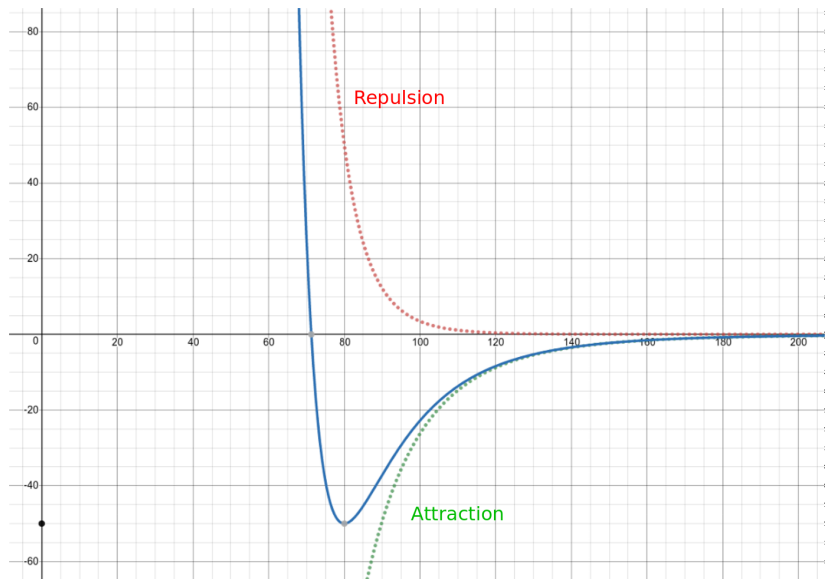
- ▶ We imagine the robot immersed in a **virtual potential field**
- ▶ The potential field is calculated through the sensors (range and bearing) of the robot
- ▶ In physics, the derivative of a potential is a **force**
- ▶ We transform the force into wheels actuation



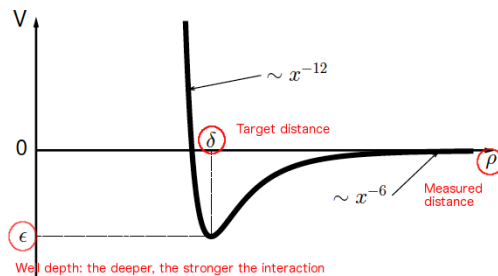
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- ▶ The potential field is calculated through the sensors (range and bearing) of the robot
- ▶ In physics, the derivative of a potential is a **force**
- ▶ We transform the force into wheels actuation
- ▶ This way, the robots tend to go to the **minimum energy configuration**

# The Lennard-Jones Potential



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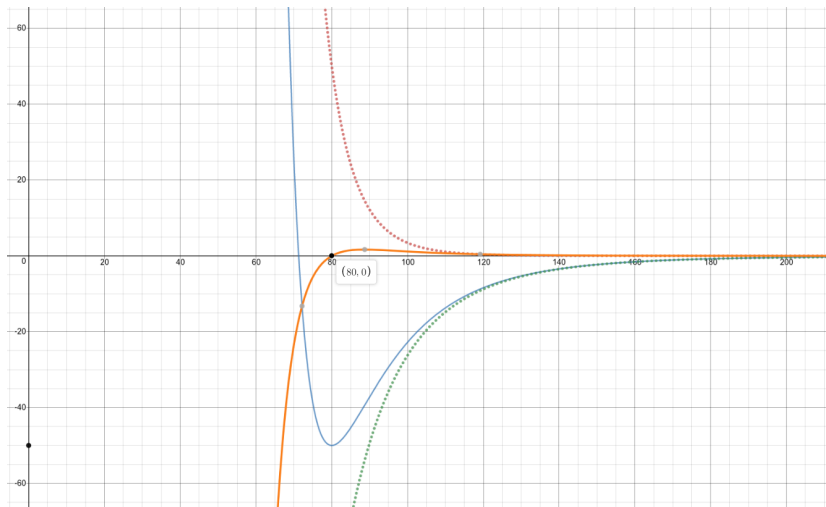
We can derive the force:

$$F(\rho) = -\nabla V(\rho) = -\frac{12\epsilon}{\rho} \left( \left( \frac{\delta}{\rho} \right)^{12} - \left( \frac{\delta}{\rho} \right)^6 \right)$$

Smaller exponential values could also work:

$$F(\rho) = -\nabla V(\rho) = -\frac{4\epsilon}{\rho} \left( \left( \frac{\delta}{\rho} \right)^4 - \left( \frac{\delta}{\rho} \right)^2 \right)$$

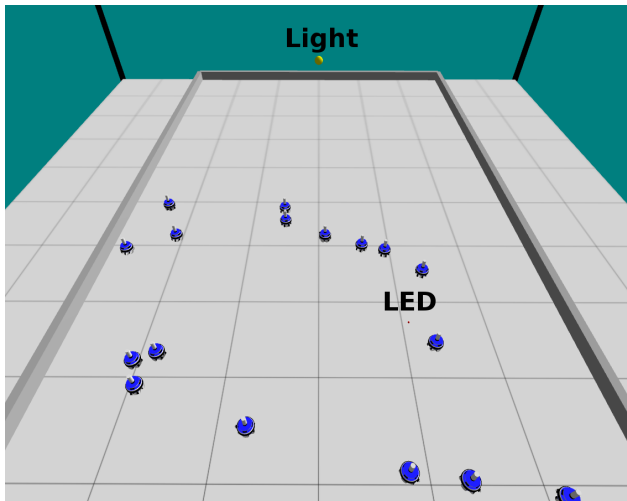
# The Lennard-Jones Potential



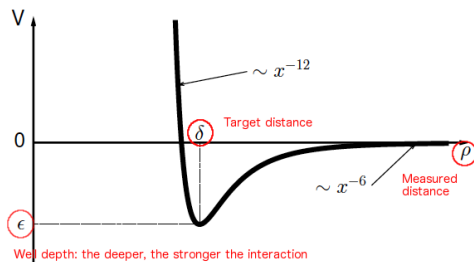
# Pattern Formation: exercise

- ▶ Step 1: Implementation local  $\rightarrow$  hexagonal pattern
- ▶ Step 2: Local + global  $\rightarrow$  circular pattern
- ▶ Step 3: Flocking

# Pattern Formation: arena



## Step 1: hexagonal pattern



$$F(\rho) = -\frac{4\epsilon}{\rho} \left( \left( \frac{\delta}{\rho} \right)^4 - \left( \frac{\delta}{\rho} \right)^2 \right)$$

1) Calculate the result force due to neighbors

for each neighbor  $i$  do

calculate Lennard-Jones[ $i$ ]

**direction** += **direction**[ $i$ ] \* Lennard-Jones[ $i$ ]

end

2) Transform **direction** into wheel actuation



## Step 2: circular pattern

The robots should:

- ▶ maintain a certain distance between each other
- ▶ create a circular pattern “around” the red LED

## Step 3: flocking

The robots should:

- ▶ maintain a certain distance between each other
- ▶ flock in a single group towards the light

Hint: it might be convenient to first create a static pattern and then start flocking