Distributed Intelligent Systems
Lab 8 Tutorial

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Lab Structure

1. Multi-robot PSO for obstacle avoidance:
   - Same fitness function as single-robot PSO
   - Differences in performance and evaluation time

2. Budget allocation:
   - Comparing standard PSO, PSO-pbest, PSO OCBA

3. Multi-robot PSO for collaborative tasks:
   - Coordinated motion: move as far as possible while staying together
Code Structure

**Pso_sup.c**

- **Main()**
  - Initialize world
  - Best = pso()
  - Evaluate best

- **Calc_fitness()**
  - Reposition robots randomly
  - Send candidate solutions to robots
  - Evaluate fitness
  - Return fitness

**Pso.c**

- **pso()**
  - Initialize swarm
  - For each iteration
    - Move particles
    - Evaluate particles
  - Return best particle

**Obs_con.c**

- **Main()**
  - Initialize robot
  - Receive weights from supervisor
  - Run controller with weights
  - Send sensor data to supervisor
Noise-resistant PSO

• **Setting NOISY=1** triggers two changes
  – Half the number of iterations
  – Reevaluate performance for lbest (with flag EVOLVE_AVG)

• You need to implement the behavior for EVOLVE_AVG
  – Modified moving average (MMA) with age as the number of periods.
  – Remember to increase age.
PSO-OCBA

- Optimal allocation of computation budget
- Very effective in the presence of noise
PSO for a collaborative task

• Fitness value to be calculated in the supervisor

• Copy-paste the noise resistant PSO

• More difficult task than obstacle avoidance

• New sources of uncertainties
Notes and Clarifications

• Simulations take longer with complex tasks, set rendering off, read ahead and answer questions while the simulation runs.

• Performance evaluations have a high variance, you may need additional runs to establish clear trends

• Remember to fill the feedback form