



This is a repository copy of *Recent Advances in Swarm Robotics*.

White Rose Research Online URL for this paper:
<http://eprints.whiterose.ac.uk/88005/>

Conference or Workshop Item:

Groß, Roderich, Gauci, Melvin, Li, Wei et al. (1 more author) (2014) Recent Advances in Swarm Robotics. In: USES 2014 - The University of Sheffield Engineering Symposium, 24 June 2014, The Octagon Centre, University of Sheffield.

10.15445/01022014.30

Reuse

Unless indicated otherwise, fulltext items are protected by copyright with all rights reserved. The copyright exception in section 29 of the Copyright, Designs and Patents Act 1988 allows the making of a single copy solely for the purpose of non-commercial research or private study within the limits of fair dealing. The publisher or other rights-holder may allow further reproduction and re-use of this version - refer to the White Rose Research Online record for this item. Where records identify the publisher as the copyright holder, users can verify any specific terms of use on the publisher's website.

Takedown

If you consider content in White Rose Research Online to be in breach of UK law, please notify us by emailing eprints@whiterose.ac.uk including the URL of the record and the reason for the withdrawal request.



eprints@whiterose.ac.uk
<https://eprints.whiterose.ac.uk/>

Recent Advances in Swarm Robotics

Roderich Groß, Melvin Gauci, Wei Li, and Jianing Chen

Department of Automatic Control and Systems Engineering, Faculty of Engineering, The University of Sheffield

Abstract

We overview recent advances in swarm robotics, particularly concerning the control of groups of autonomous robots and the identification of swarming rules through observation. Swarm intelligence is the study of systems of spatially distributed individuals that coordinate their actions in a self-organised manner and thereby exhibit complex collective behaviour [1].



Figure 1 Examples of tasks demonstrated by swarms of autonomous mobile robots. Left: A group of robots transporting a comparatively large object towards a goal location (red cylinder). Centre: A group of robots having organised themselves into a single cluster. Right: A group of robots clustering objects, simulating a litter collection scenario.

In the first part of the talk, we present our recent advances in controlling groups of robots. The platform being used is the EPFL miniature mobile robot *e-puck*. It is shown that some tasks can be solved by swarms of robots with severely limited abilities. For example, in order for a group of robots to transport a tall object (see Figure 1, Left), the robots do not fundamentally require to communicate with each other in an explicit way [2]. Rather it is sufficient if they can discriminate between the object, the goal and the remainder of the environment. In order for a group of robots to gather in a single place [3] (see Figure 1, Centre), or cluster objects that are initially dispersed [4] (see Figure 1, Right), it was found that the robots do not fundamentally require arithmetic computation. Such tasks can be solved by robots that use a binary sensor to trigger one of two possible actions, without the need to store information during run-time.

In the second part of the talk, we present a method that is able to identify models (parameters) of individuals, for example, when part of a swarm, through observation and interaction [5,6]. This method does not require any pre-defined metric to gauge the resemblance of models to observed individuals.

Research challenges in swarm robotics are manifold. They include:

- Using swarm robotic systems in real-world scenarios (e.g. Precision farming, waste management);
- Formalising the design, implementation and verification process;
- Miniaturising swarm robotic systems, for example, for applications in healthcare;
- Improving tools to learn about and influence natural swarms.

References

1. C Blum and R Groß. *Swarm intelligence in optimization and robotics: A concise introduction*, Springer Handbook of Computational Intelligence, Springer (in press)
2. J Chen, M Gauci, R Groß. *A strategy for transporting tall objects with a swarm of miniature mobile robots*, ICRA 2013, 863-869 <http://dx.doi.org/10.1109/ICRA.2013.6630674>
3. M Gauci, J Chen, W Li, TJ Dodd, R Groß. *Self-organized aggregation without computation*, International Journal of Robotics Research, OnlineFirst <http://dx.doi.org/10.1177/0278364914525244>
4. M Gauci, J Chen, W Li, TJ Dodd, R Groß. *Clustering objects with robots that do not compute*, AAMAS 2014, 421-428 <http://dl.acm.org/citation.cfm?id=2615800&CFID=454901457&CFTOKEN=66407710>
5. W Li, M Gauci, R Groß. *A coevolutionary approach to learn animal behavior through controlled interaction*, GECCO 2013, 223-230 <http://dx.doi.org/10.1145/2463372.2465801>
6. W Li, M Gauci, R Groß. *Coevolutionary learning of swarm behaviors without metrics*, GECCO 2014 (in press)

Keywords Autonomous Robots; Distributed Systems; Swarm Robotics