

Contents

List of Figures — **xiii**

List of Tables — **xvii**

List of Notations — **xix**

1 Introduction — 1

1.1 Evolutionary Robotics and Evolutionary Swarm Robotics — **4**

1.2 Further Classifications — **5**

1.3 Challenges of ER — **7**

1.4 Structure and Major Contributions of the Thesis — **9**

2 Robotics, Evolution and Simulation — 13

2.1 Evolutionary Training of Robot Controllers — **13**

2.1.1 Two Views on Selection in ER and ESR — **16**

2.1.2 Classification of Fitness Functions in ER — **18**

2.1.3 The Bootstrap Problem — **22**

2.1.4 The Reality Gap — **23**

2.1.5 Decentralized Online Evolution in ESR — **24**

2.1.6 Evolvability, Controller Representation and the Genotype-Phenotype Mapping — **26**

2.1.7 Controller Representation — **28**

2.1.8 Recombination Operators — **30**

2.1.9 Success Prediction in ESR — **30**

2.2 Agent-based Simulation — **31**

3 The Easy Agent Simulation — 35

3.1 History of the Easy Agent Simulation Framework — **36**

3.2 Basic Idea and Architectural Concept — **39**

3.2.1 Overview — **39**

3.2.2 Preliminaries — **39**

3.2.3 Classification of the Architecture — **41**

3.2.4 The SPI Architecture from an MVC Perspective — **43**

3.2.5 Comparison of the SPI Architecture with State-of-the-Art ABS Frameworks — **46**

3.3 Implementation of the SPI within the EAS Framework — **48**

3.3.1 Overview — **49**

3.3.2 Plugins — **49**

3.3.3 Master Schedulers — **51**

| | | |
|----------|--|------------|
| 3.3.4 | The classes <code>SimulationTime</code> and <code>Wink</code> — | 51 |
| 3.3.5 | The Interface <code>EASRunnable</code> — | 52 |
| 3.3.6 | “Everything is an Agent”: a Philosophical Decision — | 52 |
| 3.3.7 | Running a Simulation — | 54 |
| 3.3.8 | Getting Started — | 56 |
| 3.4 | A Comparative Study and Evaluation of the EAS Framework — | 57 |
| 3.4.1 | Method of Experimentation — | 57 |
| 3.4.2 | Results and Discussion — | 59 |
| 3.5 | Chapter Résumé — | 63 |
| 4 | Evolution Using Finite State Machines — | 65 |
| 4.1 | Theoretical Foundations — | 66 |
| 4.1.1 | Preliminaries — | 67 |
| 4.1.2 | Definition of the MARB Controller Model — | 74 |
| 4.1.3 | Encoding MARBs — | 76 |
| 4.1.4 | Mutation and Hardening — | 83 |
| 4.1.5 | Selection and Recombination — | 90 |
| 4.1.6 | Fitness calculation — | 91 |
| 4.1.7 | The Memory Genome: a Decentralized Elitist Strategy — | 96 |
| 4.1.8 | Fitness Adjustment after Mutation, Recombination and Reactivation of the Memory Genome — | 96 |
| 4.1.9 | The Robot Platforms — | 96 |
| 4.2 | Preliminary Parameter Adjustment using the Example of Collision Avoidance — | 100 |
| 4.2.1 | Specification of Evolutionary Parameters — | 101 |
| 4.2.2 | Method of Experimentation — | 101 |
| 4.2.3 | Evaluation and Discussion — | 103 |
| 4.2.4 | Concluding Remarks — | 106 |
| 4.3 | A Comprehensive Study Using the Examples of Collision Avoidance and Gate Passing — | 107 |
| 4.3.1 | Method of Experimentation — | 108 |
| 4.3.2 | Experimental results — | 111 |
| 4.3.3 | Concluding remarks — | 123 |
| 4.4 | Experiments With Real Robots — | 124 |
| 4.4.1 | Evolutionary Model — | 125 |
| 4.4.2 | Method of Experimentation — | 129 |
| 4.4.3 | Results and Discussion — | 132 |
| 4.4.4 | Concluding Remarks — | 137 |
| 4.5 | Chapter Résumé — | 138 |
| 5 | Evolution and the Genotype-Phenotype Mapping — | 139 |
| 5.1 | Overview of the Presented Approach — | 141 |

| | | |
|----------|--|------------|
| 5.2 | A Completely Evolvable Genotype-Phenotype Mapping — | 143 |
| 5.2.1 | Definition of (complete) evolvability — | 143 |
| 5.2.2 | Properties of ceGPM-based genotypic encodings — | 145 |
| 5.2.3 | The Translator Model MAPT and the Course of Evolution — | 146 |
| 5.2.4 | Genotypic and Phenotypic Spaces — | 156 |
| 5.2.5 | Evolutionary Operators — | 158 |
| 5.3 | Evaluation of the Proposed Evolutionary Model — | 162 |
| 5.3.1 | First Part – Method of Experimentation — | 163 |
| 5.3.2 | First Part – Results and Discussion — | 164 |
| 5.3.3 | Second Part – An Alternate Completely Evolvable Genotype-Phenotype Mapping and its Effects on Evolvability — | 170 |
| 5.3.4 | Second Part – Method of Experimentation — | 176 |
| 5.3.5 | Second Part – Results and Discussion — | 178 |
| 5.3.6 | Third Part – Method of Experimentation — | 181 |
| 5.3.7 | Third Part – Results and Discussion — | 182 |
| 5.4 | Chapter Résumé — | 185 |
| 6 | Data Driven Success Prediction of Evolution in Complex Environments — | 187 |
| 6.1 | Preliminaries — | 189 |
| 6.2 | A Model Capturing Completely Implicit Selection — | 193 |
| 6.2.1 | Two Parents per Reproduction (CIS-2) — | 193 |
| 6.2.2 | Eventually Stable States ($k=2$) — | 195 |
| 6.2.3 | Tournament size k — | 197 |
| 6.2.4 | Eventually Stable States (arbitrary k) — | 200 |
| 6.3 | Extending the CIS Model to Capture Explicit Selection — | 200 |
| 6.4 | Experiments — | 204 |
| 6.4.1 | Evolutionary setup — | 206 |
| 6.4.2 | Experimental Results Using the EIS Model — | 207 |
| 6.4.3 | Remarks on Evolution in the scope of the CIS Model — | 212 |
| 6.5 | Chapter Résumé — | 216 |
| 7 | Conclusion — | 219 |
| | References — | 227 |
| | Index — | 241 |