



Evolution of 2D virtual mechanical systems

Jarek Sporysz

jaroslaw.sporysz@gmail.com

Cracow University of Technology,

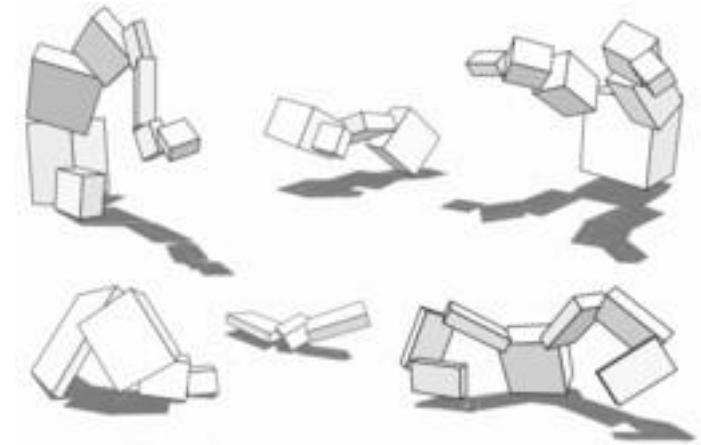
ShanghAI Lectures

2014

Inspiration

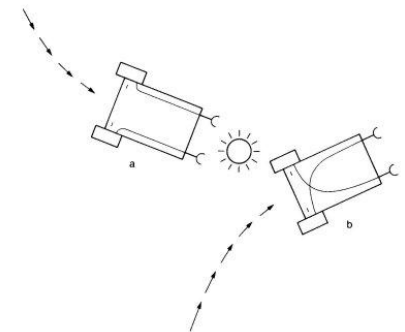
- Karl Sims: **Evolved virtual creatures**

digital media artist, computer graphics research scientist,
experiment on evolving flying, walking, jumping
and target tracking virtual agents



- Valentino Braitenberg: **Braitenberg vehicles**

Italian Neuroscientist and Cyberneticist,
hypothetical analog vehicles
built using interconnected sensors and actuators





2D Physics Engine

- Built from scratch (C/C++)
- Articulated rigid body dynamics
- Impulse based solver (Box2D, Chipmunk 2D, Physix, Bullet)
- Springs, motors, linear actuators, impulse engines (jet-like)
- Energy dissipation / energy consumption control
- Aerodynamic drag



Agents - Mobile Units

- Articulated rigid body mechanical systems
- Logics controlled by custom / internal scripting language
- You can build a Mobile Unit with:
 - Construction elements / passive joints
 - Propulsion: motors, actuators, impulse engines
 - Sensors: contact, distance, gyro-pos, proximity
 - Virtual CPU (internal assembly-like language)
- No Neural Networks (to be done)



Scripting Language

- Assembler Interpreter
- Lo-level / Built-in / C++ -> Fast
- Atom instructions
- Runtime execution visualization
- Interrupts from Agent connected devices (sensors)

```
DEVCTL "GPS1", DEV_CTL_GYROPOS_SENSOR_GET_POSITION, "POS"
DEVCTL "GPS1", DEV_CTL_GYROPOS_SENSOR_GET_VELOCITY, "VEL"
DEVCTL "GPS1", DEV_CTL_GYROPOS_SENSOR_GET_ANGLE, "ANG"
DEVCTL "GPS1", DEV_CTL_GYROPOS_SENSOR_GET_ANGVELOCITY, "ANGV"
P7: VGETX "POSX", "POS"
    FMUL "XLIMIT", -1.0, REG_FC
    JGT "POSX", "XLIMIT", "P8"
    JLT "POSX", REG_FC, "P8"
    JMP "P51"
P8: MOV REG_FB, "LOANGOUT"
    JLT "POSX", REG_FC, "P6"
    FSUB 2*PI, REG_FB, REG_FC
    JLT "ANG", PI/2, "P3"
    JGT "ANG", REG_FC, "P3"
    JMP "P51"
P3: DEVCTL "IMP1", DEV_CTL_JET_SET_IMPULSE_FREQ, "LFRQ"
    DEVCTL "IMP2", DEV_CTL_JET_SET_IMPULSE_FREQ, "HFRQ"
    JMP "P1"
```

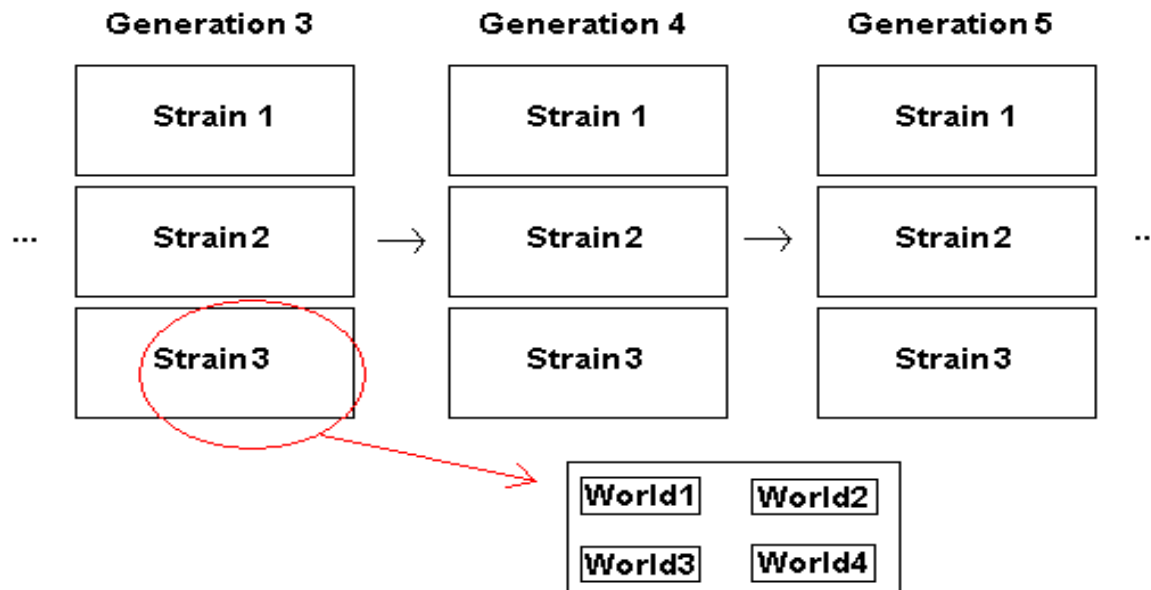


Mobile Unit genotype

- Parametric Mobile Unit definition
- Parametrization of:
 - Construction element dimensions
 - Joint mount points, joint work parameters
 - Propulsion work parameters
 - Sensor work parameters
 - Virtual CPU data variables parametrization
- Defined MU Scheme is used to build a genome
 - Each predefined MU parameter can be turned into a gene

GA Model

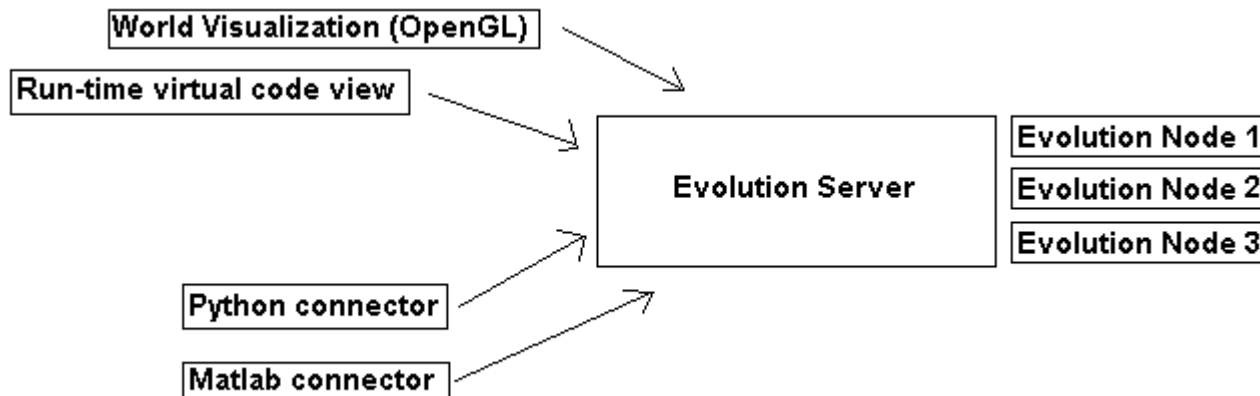
- Parallel generations (strains)
- Single / multiple agents per simulation world
- Crossover
- Mutation
- Custom generation-depth during selection





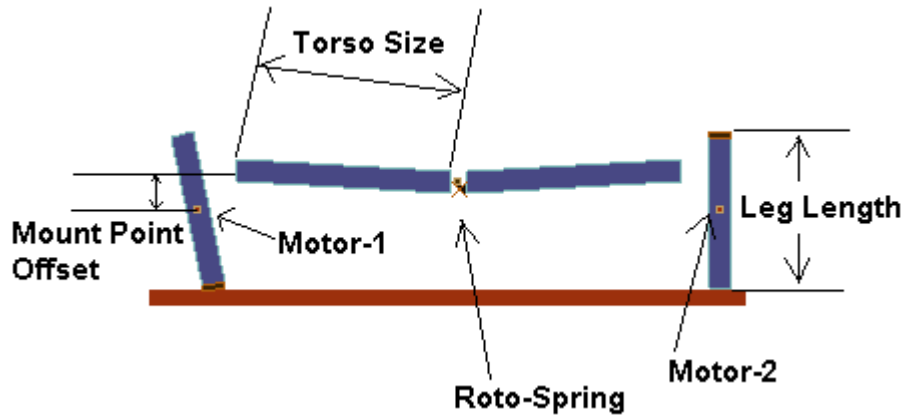
Evolution Server

- Distributed client-server system
- Paralell computation enabled Evolution Server (for supercomputing)
- One CPU / Core per one simulation world
- Different species evolutions on same server simultaneously
- Local/remote client connections (using TCP/IP networking)



First Tests: „Walkers”

„Walker” species test results

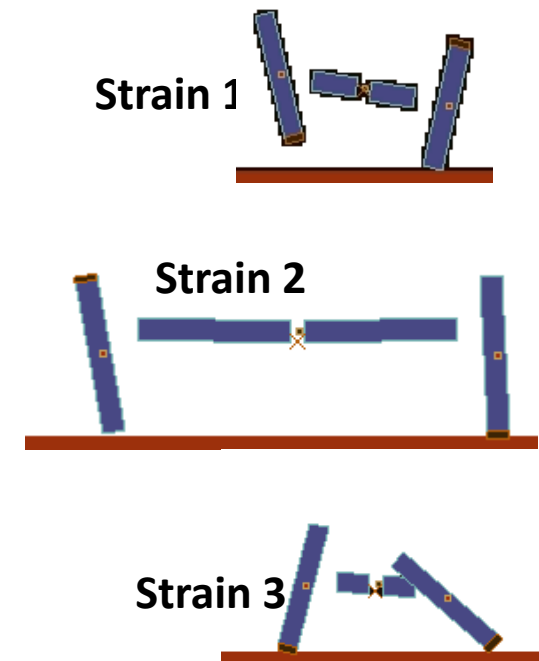
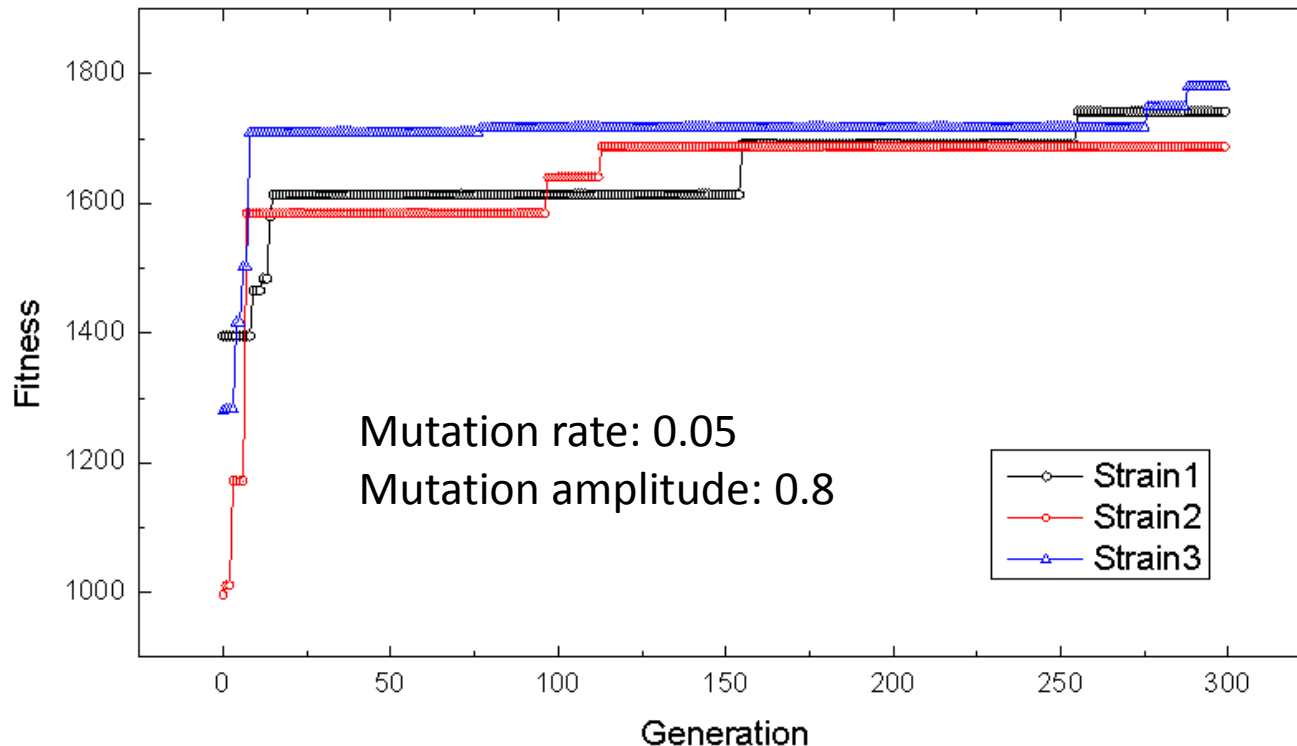


Walker Genotype:

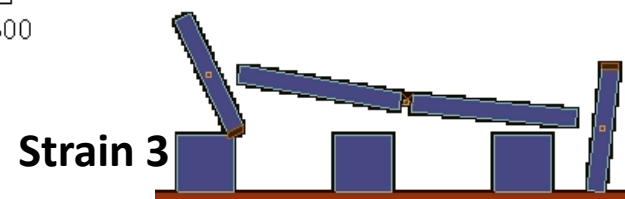
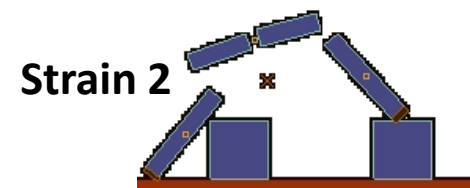
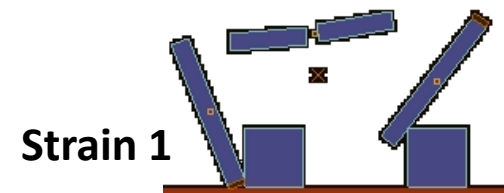
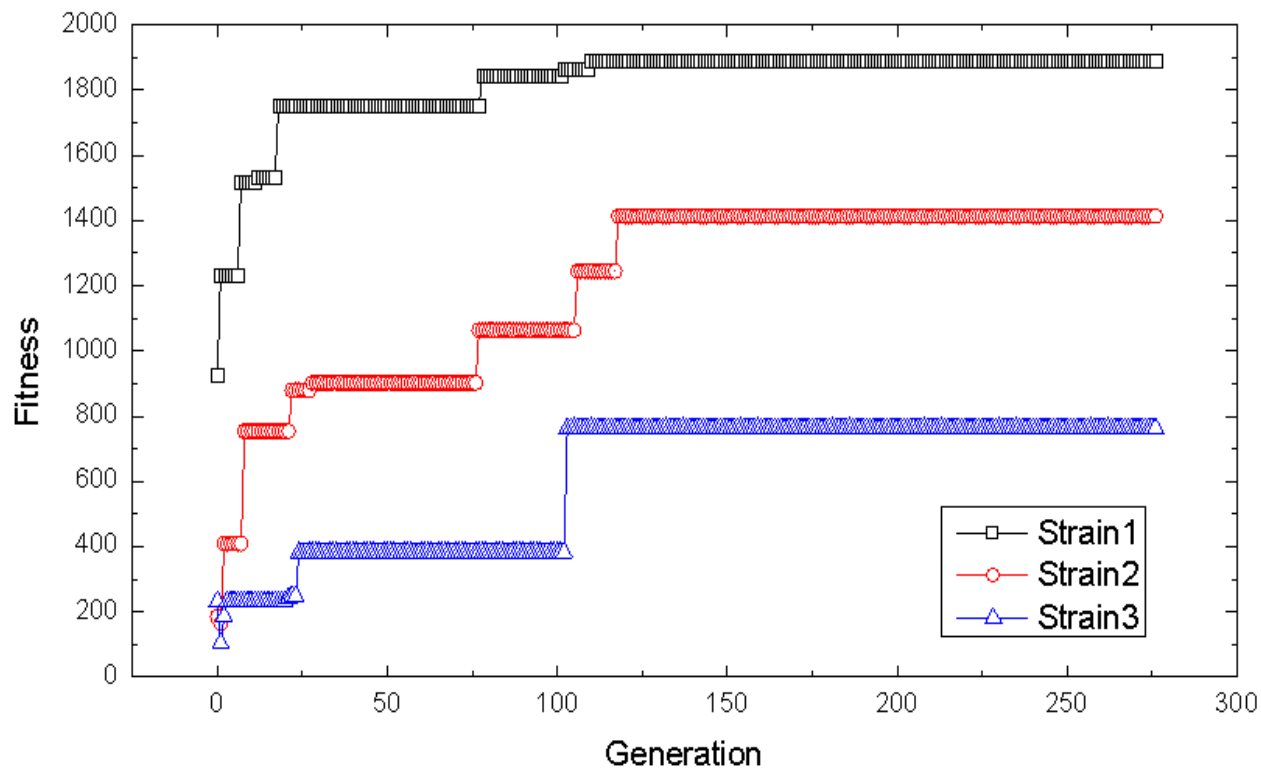
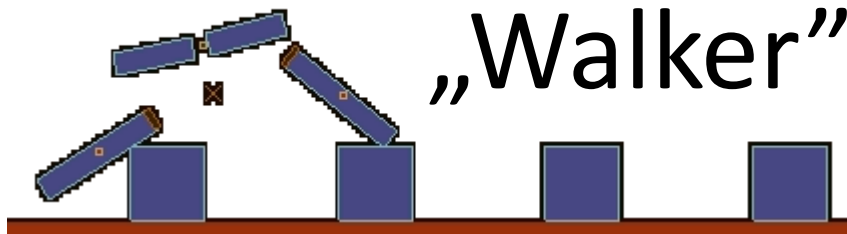
Gene1: **TorsoSize**

Gene2: **MountPointOffset**

Gene3: **LegLength**



„Walker” + obstacles



„Drone” species test

Drone Genotype:

Gene1: **Impulse magnitude**

Gene2: **High impulse frequency**

Gene3: **Low impulse frequency**

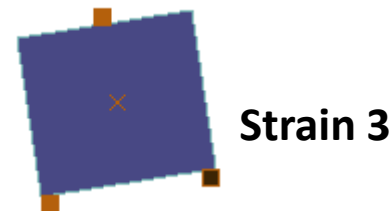
Gene4: **Fly-Limit-X**

Gene5: **Thrust-Limit-Y**

Gene6: **Critical angle**

Gene7: **Body width**

Gene8: **Body height**





Ok...What did just happened... ?

- „Walker” species using motor-torque vibration bug for faster movement
- „Drone” species using non-continous collission detection bug to cheat on flying ability
- They are all cheating !
- ... or are they not



Future work

- 2D -> 3D
- Mechanisms for new morphology emergence
- Implementation of NN as a Mobile Unit device
- More sophisticated propulsion devices
- Inter-motor synchronization (gestures)
- New sensor types
- Phenotype / Genotype Database
- Phenotype Explorer
- Evolve creatures !