b_{j-1}

b_j

b_i

b_{i+1}

b_m

b_{m+1}

b_{n-1}

b_n

Road network

L_{j,k_2}

$T_{k_3,m}$

Road network

Road network

$T_{k_1,j}$

Depot

L_{n,k_4}

Majic A Java Application For Controlling Multiple Heterogeneous Robotic Agents

Yue Wang,Eloy Garcia,David Casbeer,Fumin Zhang

Majic A Java Application For Controlling Multiple Heterogeneous Robotic Agents:

MAJIC: A Java Application for Controlling Multiple, Heterogeneous Robotic Agents ,2007 Current capability to command and control a team of heterogeneous robotic agents is limited by proprietary command formats and operating systems A specific challenge in this context is the specification the programming and the testing of software for such a wide variety of mobile robot teams This work explores the applicability of an application program interface API called the Multi Agent Java Interface Controller MAJIC that supports command control and coordination of heterogeneous robot teams MAJIC encapsulates scripted commands preprogrammed behaviors and simultaneous multi agent control By exploiting the powerful techniques of polymorphism and object oriented programming a generic MajicBot class will provide the necessary level of abstraction between the user and the proprietary architectures Utilizing the technique of inheritance future NPS students will be able to extend the generic class in order to easily add new robot specific libraries Students will also be able to utilize the existing libraries to program and test their own robot behaviors in real world environments utilizing the MAJIC package A final display of the versatility and power of programming behaviors within the MAJIC software architecture is demonstrated by a series of example programs conducted on a team of robots consisting of a Sony Aibo a Mobile Robots Pioneer and a K Team Hemisson   **Innovations and Advances in Computing, Informatics, Systems Sciences, Networking and Engineering** Tarek Sobh,Khaled Elleithy,2014-11-07 Innovations and Advances in Computing Informatics Systems Sciences Networking and Engineering This book includes a set of rigorously reviewed world class manuscripts addressing and detailing state of the art research projects in the areas of Computer Science Informatics and Systems Sciences and Engineering It includes selected papers from the conference proceedings of the Eighth and some selected papers of the Ninth International Joint Conferences on Computer Information and Systems Sciences and Engineering CISSE 2012 Includes chapters in the most advanced areas of Computing Informatics Systems Sciences and Engineering Accessible to a wide range of readership including professors researchers practitioners and students   **Multi-Agent Programming:** Rafael H. Bordini,Mehdi Dastani,Jürgen Dix,Amal El Fallah Seghrouchni,2009-06-13 Multi Agent Systems are a promising technology to develop the next generation open distributed complex software systems The main focus of the research community has been on the development of concepts concerning both mental and social attitudes architectures techniques and general approaches to the analysis and specification of multi agent systems This contribution has been fragmented without any clear way of putting it all together rendering it inaccessible to students and young researchers non experts and practitioners Successful multi agent systems development is guaranteed only if we can bridge the gap from analysis and design to effective implementation Multi Agent Programming Languages Tools and Applications presents a number of mature and influential multi agent programming languages platforms development tools and methodologies and realistic applications summarizing the state of the art in an accessible manner for professionals and computer science students at all levels   **Multiple Agent**

Architecture for a Multiple Robot System [electronic Resource] Bram Aaron Bakst Gruneir,2005 Controlling systems with multiple robots is quickly becoming the next large hurdle that must be overcome for groups of robots to successfully function as a team An agent oriented approach for this problem is presented in this thesis By using an agent oriented method the robots can act independently yet still work together To be able to establish communities of robots a basic agent oriented control system for each robot must first be implemented This thesis introduces a novel method to create Physical Robot Agents promoting a separation of cognitive and reactive behaviours into a two layer system These layers are further abstracted into key subsections that are required for the Physical Robot Agents to function To test this architecture experiments are performed with physical robots to determine the feasibility of this approach A real time implementation of a Physical Robot Agent would greatly expand its field of use The speed of internal communication is analyzed to validate the application of this architecture to real time tasks It is concluded that the Physical Robot Agents are well suited for multiple robot systems and that real time applications are feasible **Cooperative Control of Multi-Agent Systems** Yue Wang,Eloy Garcia,David Casbeer,Fumin Zhang,2017-03-20 A comprehensive review of the state of the art in the control of multi agent systems theory and applications The superiority of multi agent systems over single agents for the control of unmanned air water and ground vehicles has been clearly demonstrated in a wide range of application areas Their large scale spatial distribution robustness high scalability and low cost enable multi agent systems to achieve tasks that could not successfully be performed by even the most sophisticated single agent systems Cooperative Control of Multi Agent Systems Theory and Applications provides a wide ranging review of the latest developments in the cooperative control of multi agent systems theory and applications The applications described are mainly in the areas of unmanned aerial vehicles UAVs and unmanned ground vehicles UGVs Throughout the authors link basic theory to multi agent cooperative control practice illustrated within the context of highly realistic scenarios of high level missions without losing site of the mathematical background needed to provide performance guarantees under general working conditions Many of the problems and solutions considered involve combinations of both types of vehicles Topics explored include target assignment target tracking consensus stochastic game theory based framework event triggered control topology design and identification coordination under uncertainty and coverage control Establishes a bridge between fundamental cooperative control theory and specific problems of interest in a wide range of applications areas Includes example applications from the fields of space exploration radiation shielding site clearance tracking classification surveillance search and rescue and more Features detailed presentations of specific algorithms and application frameworks with relevant commercial and military applications Provides a comprehensive look at the latest developments in this rapidly evolving field while offering informed speculation on future directions for collective control systems The use of multi agent system technologies in both everyday commercial use and national defense is certain to increase tremendously in the years ahead making this book a valuable resource for researchers

engineers and applied mathematicians working in systems and controls as well as advanced undergraduates and graduate students interested in those areas **The Application of a Multi-agent System for the Realisation of Intelligent Robotic Control** Kristan Dyson,University of the West of England,2007 **A Reconfigurable Cooperative Control System for Rapid Deployment of Multi-robot Systems** Stephen Sodokan Nestinger,2009 Multi robot systems have been used in a vast array of fields and are of particular interest in perilous environments Utilizing multiple smaller and cheaper robots have many advantages compared to a highly specialized single robot Multi robot systems are fault tolerant by nature and provide task completion parallelism for faster mission completion One of the main issues in multi robot systems is the lack of a common set of abstractions and middleware Controlling and programming cooperative multi robot systems is a highly complicated task that requires a flexible and agile control architecture and programming environment that are able to handle the distributed nature of multi robot system This dissertation studies many different aspects of multi robot systems The major characteristics different paradigms and programmability of multi robot systems are presented The key aspects of cooperative multi robot systems are discussed along with the different methods in which cooperation is implemented The use of mobile agents to provide multi robot system reconfigurability reprogrammability and rapid deployment is introduced Several multi robot system middleware are discussed along with specialized middleware for cooperative systems A highly flexible and reconfigurable cooperative robot control platform called Mobile R has been developed in the course of this research Mobile R consists of two modules the Robot Control System RCS and Deployment System DS Mobile R is a highly extensible platform that follows the multi agent paradigm It allows for the implementation of architectures popularly used in the different multi robot paradigms and is based on widely accepted standards for multi agent interaction allowing for interoperability with other multi agent systems Mobile R is built upon Mobile C an IEEE Foundation for Intelligent Physical Agents standards compliant mobile agent system The innate mobility characteristic of mobile agents provides an invariant execution of control code over disparate hosts and overall system fault tolerance The system has been validated through multiple experiments presented in the dissertation The simulated application of Mobile R to tier scalable planetary reconnaissance demonstrates the feasibility and applicability of the system to various multi robot scenarios **Distributed Control of Multi-agent Systems Under Communication Constraints** Syed Ali Ajwad,2020 Multi agent systems MAS have gained much popularity due to their vast range of applications MAS is deployed to achieve more complex goals which could not be realized by a single agent alone Communication and information exchange among the agents in a MAS is crucial to control its cooperative behavior Agents share their information with their neighbors to reach a common objective thus do not require any central monitoring unit However the communication among the agents is subject to various practical constraints These constraints include irregular and asynchronous sampling periods and the availability of partial states only Such constraints pose significant theoretical and practical challenges In this thesis we investigate two fundamental problems

related to distributed cooperative control namely consensus and formation control of double integrator MAS under these constraints It is considered that each agent in the network can measure and transmit its position state only at nonuniform and asynchronous sampling instants Moreover the velocity and acceleration are not available First we study the problem of distributed control of leader following consensus A continuous discrete time observer based leader following algorithm is proposed The observer estimates the position and velocity of the agent and its neighbor in continuous time from the available sampled position data Then these estimated states are used for the computation of the control input Both fixed and switching topology scenarios are discussed Secondly a consensus based distributed formation tracking protocol is designed to achieve both fixed and time varying formation patterns Collision avoidance problem is also studied in this thesis An Artificial Potential Function APF based collision avoidance mechanism is incorporated with the formation tracking algorithm to prevent collisions between the agents while converging to a desired position Finally the proposed algorithms are applied on a multi robot network consisting of differential drive robots using Robot Operating System ROS A new scheme is proposed to deal with nonholonomic constraints of the robot Efficiency of the designed algorithms and their effectiveness in real world applications are shown through both simulation and hardware results <u>Cooperative Manipulation, Swarming and Connectivity Control of Multi-agent Mechanical Systems</u> Aykut C. Satici,University of Texas at Dallas. Graduate Program in Electrical Engineering,2014 Many of the robotic tasks that is performed by single robotic mechanisms may be performed more efficiently cheaply and robustly by using teams of robotic agents **A Mobile Agent-based Framework for Automatic Coordination of Autonomous Multi-robot Systems** Binsen Qian,2018 Robots can protect humans from risk in many applications such as search and rescue outer space exploration and toxic cleanup Multi robot systems have a huge potential to benefit versatile applications through reconfiguring heterogeneous or homogeneous robots in different ways This includes combining different capabilities for heterogeneous systems and forming different physical configurations for homogeneous systems Additionally multi robot systems can reduce overall time consumption by pursuing goals by parallel execution For example for those applications that contain spatially separate tasks multiple robot groups can work in different locations simultaneously and therefore improve the performance in terms of time More importantly due to the multiple agents and data sharing the entire system is more fault tolerance While having these advantages it also raises numerous software design challenges such as communication task assignment and resource conflicts Ideally a cooperation framework needs to be robust adaptable efficient and flexible to an extent This research thesis presents the design and implementation of RoboCoop a mobile agent based framework for automatic coordination of multi robot systems RoboCoop consists of several modules such as knowledge base Input Output task procession execution and sensor reading The agent based framework utilizes the innate advantages of the multi threading of each agent such that each module can run persistently without blocking others Modules can exchange information and data through inter agent communication based on the

standards of the Foundation for Intelligent Physical Agents FIPA The presented framework allows robots to coordinate manage and execute tasks automatically Also a backup mechanism is developed to ensure the robustness of robot systems Moreover it allows customized algorithms and strategies for task allocation and execution Three case studies have been completed with three different robots Linkbot CPSBot and Lego Mindstorms NXT EV3 to demonstrate the potentials of the framework In the box pushing application there are over sized boxes that require two robots pushing simultaneously to make it move straight which demonstrates the ability of synchronization of RoboCoop Then the field mapping application illustrates how robots can work in parallel to reduce completion time for missions that can be split into subsets Finally the robot soccer not only shows the use of sensor fusion in robot localization but also illustrates the cooperation of two teammates to complete a free kick

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Table of Contents Majic A Java Application For Controlling Multiple Heterogeneous Robotic Agents

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