EVOLUTIONARY TASK FORCE

SUMMARY OF WEEK 14

Integration of the various approaches has continued the past week. A preliminary design for the integration has been created by Jean-Marc and can be seen in Figure 1. The idea behind the design is to integrate the various stages of a robots life: swarm-mode, morphogenesis, organism-mode, and dying, through a common structure.

The design implements a supervisor which is in charge of communicating between robots, gathering information from sensors, and driving actuators. It delegates the control for the various stages to specialized controllers as have been developed by the various sub-task forces.

As mentioned last week Wenguo is going to work on a demonstration of his approach in real hardware, he therefore handed over his code to Berend and Christopher. Berend is working on removing the stage shortcut, while Christopher has rewritten the explicit representation so it is cleaner and easier to use.

The organism controllers are almost fully integrated; only Yao Yao's method is not yet fully integrated, but is underway.

Lastly Vojta has set up a page where the available hardware for running experiments is maintained. He is also looking for more resources which can be used.

For further details please consult the SEC Blog: https://symbrion-ec.wikidot.com

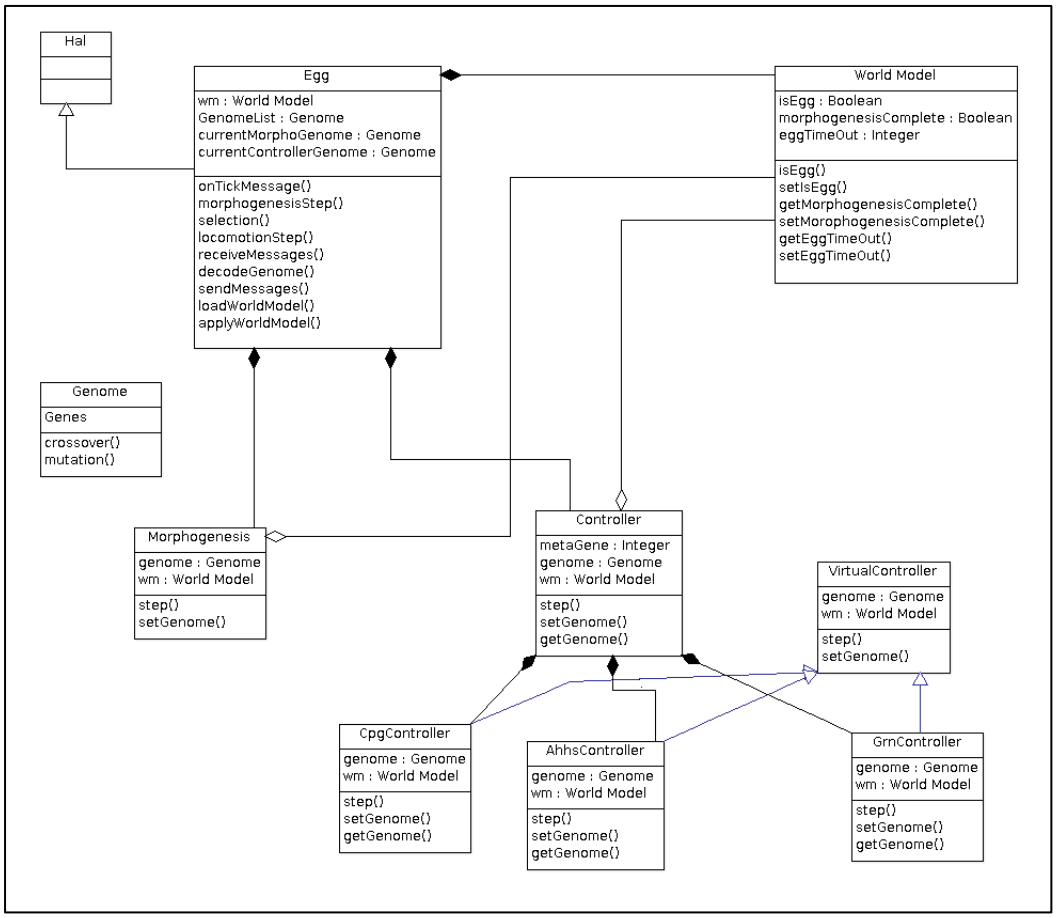

FIGURE 1 CLASS UML-DIAGRAM OF THE PRELIMINARY INTEGRATION DESIGN