

# **Studies in Computational Intelligence**

Volume 690

## **Series editor**

Janusz Kacprzyk, Polish Academy of Sciences, Warsaw, Poland  
e-mail: [kacprzyk@ibspan.waw.pl](mailto:kacprzyk@ibspan.waw.pl)

### *About this Series*

The series “Studies in Computational Intelligence” (SCI) publishes new developments and advances in the various areas of computational intelligence—quickly and with a high quality. The intent is to cover the theory, applications, and design methods of computational intelligence, as embedded in the fields of engineering, computer science, physics and life sciences, as well as the methodologies behind them. The series contains monographs, lecture notes and edited volumes in computational intelligence spanning the areas of neural networks, connectionist systems, genetic algorithms, evolutionary computation, artificial intelligence, cellular automata, self-organizing systems, soft computing, fuzzy systems, and hybrid intelligent systems. Of particular value to both the contributors and the readership are the short publication timeframe and the worldwide distribution, which enable both wide and rapid dissemination of research output.

More information about this series at <http://www.springer.com/series/7092>

Peter Simon Sapaty

# Managing Distributed Dynamic Systems with Spatial Grasp Technology



Springer

Peter Simon Sapaty  
Institute of Mathematical Machines  
and Systems  
National Academy of Sciences  
Kiev  
Ukraine

ISSN 1860-949X ISSN 1860-9503 (electronic)  
Studies in Computational Intelligence  
ISBN 978-3-319-50459-9 ISBN 978-3-319-50461-2 (eBook)  
DOI 10.1007/978-3-319-50461-2

Library of Congress Control Number: 2016963177

© Springer International Publishing AG 2017

This work is subject to copyright. All rights are reserved by the Publisher, whether the whole or part of the material is concerned, specifically the rights of translation, reprinting, reuse of illustrations, recitation, broadcasting, reproduction on microfilms or in any other physical way, and transmission or information storage and retrieval, electronic adaptation, computer software, or by similar or dissimilar methodology now known or hereafter developed.

The use of general descriptive names, registered names, trademarks, service marks, etc. in this publication does not imply, even in the absence of a specific statement, that such names are exempt from the relevant protective laws and regulations and therefore free for general use.

The publisher, the authors and the editors are safe to assume that the advice and information in this book are believed to be true and accurate at the date of publication. Neither the publisher nor the authors or the editors give a warranty, express or implied, with respect to the material contained herein or for any errors or omissions that may have been made. The publisher remains neutral with regard to jurisdictional claims in published maps and institutional affiliations.

Printed on acid-free paper

This Springer imprint is published by Springer Nature  
The registered company is Springer International Publishing AG  
The registered company address is: Gewerbestrasse 11, 6330 Cham, Switzerland

*To my grandson Vanya with true belief that  
the world he so much loves and needs can be  
secured and improved by this book*

# Preface

This is the third book on high-level ideology, model, and technology for solving tasks in large distributed networked systems by active scenarios navigating and matching them in parallel. The other two being *Mobile Processing in Distributed and Open Environments* (1999) and *Ruling Distributed Dynamic Worlds* (2005), both from John Wiley & Sons.

The naturally arising question: What changed from the time of previous publications, and why this new book may be needed now? At least five reasons can be named.

*Reason 1.* Changed is the world as a whole, with its dynamics grown enormously for the last decade, lavishly fed by numerous conflicts and crises including international terrorism, ethnic, religious and military conflicts, endless floods of refugees, economy collapses too. To withstand this dynamics, much updated and even completely different views on the problems and their solutions are needed, in the area of information and control models and technologies too.

*Reason 2.* After the second book's publication, the developed ideology, methodology and technology were severely tested at many world events, both civil and military, to evaluate their potentials for solving hard practical tasks in distributed dynamic systems. And the proposed approach pretty much survived and was of real interest to different audiences. The feedback and experience gained helped to improve the technology and especially its core language in comparison with the previous book publications.

*Reason 3.* The participation in different world events with very different topics and very dissimilar audiences helped to witness uniformity of basic system principles in all areas. And this encouraged an attempt to link our work with some fundamental concepts like General System Theory, System Dynamics, Gestalt Psychology, also new trends like Memetics and Human Terrain; stimulating in this respect was our presentation at Gestalt Psychology Congress in Germany. It became clear that moving to higher system levels can often drastically improve solutions at lower levels too.

*Reason 4.* The previous technology versions were prototyped using special software communication channels between computers. But the current version can

use any existing media communications, and can be easily installed in popular electronic devices which, communicating under the spreading spatial scenarios can help to solve different social problems within or without any borders.

*Reason 5.* Many conference and journal publications appeared during the last decade in relation to this technology and applications. It would be useful to collect at least most important of them and present in extended and improved form within a single volume like a book.

The mentioned above, altogether, have inspired the author to prepare this book in hope it can be useful and enjoyable by readers. Wishing them luck in digesting this material, with readiness to provide any additional consultation and information.

Kiev, Ukraine

Peter Simon Sapaty

# Acknowledgements

The following persons and organizations contributed to the development of ideas and experience expressed in the current book.

Roland Vollmar, Institute of Theoretical Informatics, Karlsruhe, Germany, as the author's supervisor within Alexander von Humboldt Foundation (AvH) award and related projects carried out at the universities of Braunschweig, Karlsruhe, and Oxford UK. His high scientific and moral standards and ardent support of novel concepts proved crucial in the development of ideas preceding this book.

Werner Zorn, Hasso-Plattner-Institut of the University of Potsdam, Germany, with whom the author supervised Intelligent Network Management project at the University of Karlsruhe financed by Siemens Nixdorf. High-level solutions for management of distributed computer networks were developed, related to this book too.

Lubomir Bic, School of Information and Computer Science, University of California, Irvine, USA, and Son Vuong, University of British Columbia Canada, who provided support of the author's works on parallel and distributed computing and hosted demonstration of the developed WAVE system at UCI and UBC.

Masanori Sugisaka, ALife Robotics, Japan, with whom the author has long and fruitful cooperation in the area of Artificial Life and Robotics, from working at the Oita University to organizing international ALIFE conferences to the grant of Japan Society for the Promotion of Science (JSPS), also having common publications mentioned in the book.

Stephen Lambacher, School of Social Informatics, Aoyama Gakuin University in Tokyo Japan, a great linguist with whom the author discussed many original ideas preceding this book, in direct contacts when worked together at the University of Aizu-Wakamatsu, and afterwards by email.

Robert Finkelstein, Robotic Technology Inc., USA, a great roboticist with whom the book related ideas were frequently discussed for more than a decade, some resulted in common publications mentioned in the book. Exchanges of opinion on memetics, human terrain, psychology, philosophy, social engineering, politics, system management, military to civilian conversion, etc. were inspiring.

Jürgen Kriz, University of Osnabrück, a great philosopher, who supported the author's ideas on holistic vision of large distributed systems and their relevance to Gestalt psychology, expressed in the book and presented at international Gestalt Theory Congress.

Bob Nugent, a retired US Navy Commander, with whom the author had meetings and useful discussions on advanced command and control, especially in maritime and underwater area, which inspired the author to show exemplary robotic scenarios in the book confirming advantages of the technology developed.

Very productive was cooperation within editorial boards of a number of international scientific journals which also organized invited publications of the book related papers. Special thanks to Svitlana Tymchyk and Natalia Karevina, Mathematical Machines and Systems journal (ISSN 1028-9763) of National Academy of Sciences in Ukraine, for friendship and lasting support. Similar thanks to Journal of Computer Science & Systems Biology, JCSB (ISSN: 0974-7230), International Journal of Advanced Research in Artificial Intelligence (IJARAI) of Science and Information (SAI) Organization (ISSN: 2165-4069, 2165-4050), and International Relations and Diplomacy (ISSN: 2328-2134).

The author is always grateful to his father Simon, a known biologist in the past, who researched in the area of photosynthesis of plants and lectured at Agricultural Academy in Ukraine, for taking his son from the early childhood and for all life into the scientific world of light, life, and growth. The current book has emerged from this wonderful world too.

# Contents

<b>1</b>	<b>Introduction</b> . . . . .	1
1.1	What Is This Book About? . . . . .	1
1.2	Offering Technological Response to World Challenges . . . . .	1
1.3	Background and History . . . . .	2
1.3.1	Creating Distributed Networks . . . . .	2
1.3.2	Using Program Mobility . . . . .	2
1.3.3	Active Graphs and Networks . . . . .	3
1.3.4	Mobile Programs in Active Networks . . . . .	3
1.3.5	International Support . . . . .	4
1.4	The Book Organization . . . . .	5
	References . . . . .	8
<b>2</b>	<b>Some Theoretical Background</b> . . . . .	11
2.1	Introduction . . . . .	11
2.2	General Systems Theory . . . . .	11
2.3	System Dynamics . . . . .	13
2.4	Gestalt Psychology . . . . .	15
2.5	Memetics Versus Genetics . . . . .	20
2.6	Brain Waves and Consciousness . . . . .	21
2.7	Interoperability Organizations and Their Weakness . . . . .	23
2.8	Over-Operability Versus Interoperability in System Organization . . . . .	25
2.9	Conclusion . . . . .	28
	References . . . . .	28
<b>3</b>	<b>Spatial Grasp Model</b> . . . . .	31
3.1	Introduction . . . . .	31
3.2	Spatial Grasp Model Key Issues . . . . .	32
3.2.1	General Idea . . . . .	32
3.2.2	Parallel Wavelike World Coverage . . . . .	32

3.2.3	Navigation Pattern's Modification, Reduction, and Replication . . . . .	33
3.2.4	Spatial Grasp with Echo Processing . . . . .	33
3.2.5	Multisource Matching . . . . .	35
3.2.6	Combining Biological, Sociological, and Psychological Ideas . . . . .	36
3.3	General Organization of Spatial Grasp Language, SGL . . . . .	36
3.3.1	SGL Orientation and Peculiarities . . . . .	36
3.3.2	SGL Recursive Structure . . . . .	37
3.3.3	Constants . . . . .	37
3.3.4	Variables . . . . .	38
3.3.5	Rules . . . . .	38
3.4	More SGL Details . . . . .	38
3.4.1	SGL Worlds . . . . .	39
3.4.2	How SGL Scenarios Evolve . . . . .	39
3.4.3	Sense and Nature of SGL Rules . . . . .	40
3.4.4	The Use of SGL Variables . . . . .	41
3.4.5	SGL Control States and Their Hierarchical Merge . . . . .	42
3.5	Elementary Examples in SGL . . . . .	43
3.6	General Issues of SGL Networked Interpretation . . . . .	52
3.7	Conclusion . . . . .	53
	References . . . . .	54
<b>4</b>	<b>SGL Detailed Specification . . . . .</b>	<b>57</b>
4.1	Introduction . . . . .	57
4.2	Full SGL Syntax and Main Constructs . . . . .	57
4.3	SGL Constants . . . . .	60
4.3.1	Information . . . . .	60
4.3.2	Physical Matter . . . . .	60
4.3.3	Custom Constants . . . . .	61
4.3.4	Special Constants . . . . .	61
4.3.5	Compound Constants, Grasps . . . . .	62
4.4	SGL Variables . . . . .	62
4.4.1	Global, Heritable, Frontal, and Nodal Variables . . . . .	62
4.4.2	Environmental Variables . . . . .	62
4.5	SGL Rules . . . . .	66
4.5.1	Movement . . . . .	66
4.5.2	Creation . . . . .	67
4.5.3	Echoing . . . . .	68
4.5.4	Verification . . . . .	70
4.5.5	Assignment . . . . .	70
4.5.6	Advancement . . . . .	71
4.5.7	Branching . . . . .	72
4.5.8	Transference . . . . .	75

4.5.9	Timing . . . . .	76
4.5.10	Granting . . . . .	77
4.5.11	Type . . . . .	78
4.5.12	Usage . . . . .	78
4.5.13	Application . . . . .	79
4.5.14	Grasp . . . . .	79
4.6	Conclusion . . . . .	79
	References. . . . .	80
<b>5</b>	<b>Main Spatial Mechanisms in SGL . . . . .</b>	<b>81</b>
5.1	Introduction . . . . .	81
5.2	Progress Points or Props . . . . .	81
5.3	Single Grasp Representation . . . . .	82
5.4	Depth Mode Space Navigation . . . . .	84
5.4.1	Advancement. . . . .	84
5.4.2	Sliding . . . . .	87
5.4.3	Repetition . . . . .	88
5.5	Breadth Mode Navigation . . . . .	91
5.5.1	General Branching . . . . .	92
5.5.2	IF-THEN-ELSE Branching . . . . .	94
5.5.3	OR Branching . . . . .	94
5.5.4	AND Branching . . . . .	96
5.5.5	Repetitive Branching . . . . .	97
5.6	Breadth-Depth Combined Navigation Mode . . . . .	100
5.6.1	General Breadth-Depth Mode . . . . .	100
5.6.2	Asynchronous-Parallel Mode . . . . .	101
5.6.3	Synchronous-Parallel Mode . . . . .	102
5.7	Direct Operations on Remote Values . . . . .	103
5.8	Conclusion . . . . .	104
	References. . . . .	105
<b>6</b>	<b>SGL Networked Interpreter . . . . .</b>	<b>107</b>
6.1	Introduction . . . . .	107
6.2	The Interpreter General Organization . . . . .	108
6.3	Data Structures of the Interpreter . . . . .	108
6.3.1	Grasps Queue . . . . .	109
6.3.2	Suspended Grasps . . . . .	109
6.3.3	Track Forest . . . . .	109
6.3.4	Activated Rules . . . . .	110
6.3.5	Knowledge Network . . . . .	110
6.3.6	Grasps Identities . . . . .	110
6.3.7	Heritable Variables . . . . .	111
6.3.8	Fontal Variables. . . . .	111

6.3.9	Nodal Variables . . . . .	111
6.3.10	Environmental Variables . . . . .	112
6.3.11	Global Variables . . . . .	112
6.3.12	Incoming Queue . . . . .	112
6.3.13	Outgoing Queue . . . . .	113
6.4	Functional Processors . . . . .	113
6.4.1	Communication Processor . . . . .	113
6.4.2	Parser. . . . .	113
6.4.3	Operation Processors . . . . .	114
6.4.4	Navigation Processor. . . . .	114
6.4.5	Control Processor . . . . .	114
6.4.6	World Access Unit . . . . .	115
6.5	Track-Based Automatic Command and Control . . . . .	115
6.5.1	Track-Based Management Components . . . . .	115
6.5.2	Forward Grasping . . . . .	117
6.5.3	Distribution of Track Structure . . . . .	118
6.5.4	Echoing Via Tracks. . . . .	118
6.5.5	Failed and Blocked Track Branches . . . . .	120
6.5.6	Further World Grasping. . . . .	120
6.5.7	More Advanced Track Infrastructure . . . . .	123
6.6	Examples of Involvement of Interpreter Components . . . . .	124
6.6.1	Transferring Control Messages . . . . .	124
6.6.2	Engagement in Data Processing. . . . .	125
6.6.3	Networked Knowledge Processing. . . . .	127
6.6.4	Movement in Physical Space. . . . .	128
6.7	Integration with Other Systems. . . . .	129
6.8	Conclusions . . . . .	131
	References. . . . .	131
<b>7</b>	<b>Creation, Activation, and Management of a Distributed World. . .</b>	<b>133</b>
7.1	Introduction . . . . .	133
7.2	Distributed World Creation. . . . .	134
7.2.1	Elementary Examples . . . . .	134
7.2.2	Creating General Networks . . . . .	136
7.3	Network Distribution . . . . .	142
7.4	World's Invasion with Mobile Objects . . . . .	144
7.5	Collecting and Exhibiting the History of Navigation . . . . .	145
7.6	Adding Nodal Activity . . . . .	146
7.7	Global Supervision and Inspection . . . . .	148
7.8	Runtime Restructuring of the Active Distributed World . . . . .	150

7.9	Virtual-Physical World Creation and Management . . . . .	152
7.9.1	Converting Virtual to Physical. . . . .	152
7.9.2	Keeping Size and Shape in Movement . . . . .	153
7.9.3	Creating Physical Structures from the Start . . . . .	155
7.10	Conclusion . . . . .	156
	References. . . . .	156
<b>8</b>	<b>Parallel and Distributed Network Operations . . . . .</b>	<b>159</b>
8.1	Introduction . . . . .	159
8.2	Finding Simple Paths Between Nodes . . . . .	160
8.2.1	All Simple Paths . . . . .	160
8.2.2	Limited Length Simple Paths. . . . .	161
8.2.3	Using Constraints on Links . . . . .	161
8.2.4	Constraints on Both Links and Nodes . . . . .	162
8.2.5	Taking into Account Orientation of Links . . . . .	162
8.2.6	Issuing the Paths in the Final Node. . . . .	163
8.3	Creating Shortest Path Tree . . . . .	163
8.4	Finding Shortest Path Between Nodes . . . . .	164
8.4.1	Single Source Solution . . . . .	164
8.4.2	Two-Source Solution. . . . .	165
8.5	Moving Physical Matter via the Path Found. . . . .	166
8.5.1	Matter Moving Along the Path . . . . .	167
8.5.2	Matter Moving Opposite the Path . . . . .	167
8.6	Finding Weak and Strong Components in Networks . . . . .	168
8.6.1	Finding Weakest Points. . . . .	168
8.6.2	Finding Strongest Parts . . . . .	170
8.7	Finding Arbitrary Structures in Arbitrary Networks . . . . .	172
8.7.1	Exemplary Network and Search Template. . . . .	172
8.7.2	Template Representation Based on a Path Through All Nodes . . . . .	172
8.7.3	Template Representation Based on a Path Through All Links. . . . .	174
8.7.4	Networks with Named Nodes and Links . . . . .	175
8.7.5	Working with Networks Having Multiple Links Between Nodes . . . . .	177
8.8	Examples of Finding Particular Structures . . . . .	177
8.8.1	Example 1: Triangle . . . . .	178
8.8.2	Example 2: Two Triangles Sharing a Side. . . . .	179
8.8.3	Example 3: Unlimited Expanding Structure. . . . .	180
8.9	Conclusion . . . . .	181
	References. . . . .	181

<b>9</b>	<b>Solving Societal Problems</b>	183
9.1	Introduction	183
9.2	Social Problems and Social Networks	184
9.2.1	Social Problems Examples	184
9.2.2	Human Terrain Concept and Its Relation to Social Problems	184
9.2.3	Social Networks and Their Representation	186
9.3	Exemplary Social Network Operations	187
9.3.1	Distributed Counting of the Number of Nodes and Links	187
9.3.2	Finding Paths Between Nodes	188
9.3.3	Shortest Path Tree and Solutions Based on It	191
9.3.4	Spatial Centres of Organizations	195
9.4	Active and Assisted Living	198
9.5	Emergency Management	200
9.5.1	Investigating and Relieving Disaster Consequences	200
9.5.2	Collective Evacuation from a Disaster Zone	201
9.6	Other Societal Tasks Currently Investigated Under SGT	202
9.7	Conclusion	203
	References	203
<b>10</b>	<b>Automated Command and Control</b>	205
10.1	Introduction	205
10.2	Purely Semantic Scenario with Automatic Control	206
10.2.1	Exemplary Task	206
10.2.2	Three-Doer Task Solution	207
10.2.3	Task Solution with Other Numbers of Doers	212
10.3	Dynamic Creation of Distributed Command Infrastructures	213
10.3.1	Hierarchical Operational Infrastructure	214
10.3.2	Peripheral, Ring Infrastructure	218
10.4	Withstanding Cruise Missiles	220
10.4.1	Existing Solutions	220
10.4.2	Installing SGL Interpreters in Distributed Sensors	221
10.4.3	Distributed Missile Tracking Scenario in SGL	222
10.4.4	Withstanding Multiple Attacks	224
10.5	Networked Night Vision Scenarios	226
10.5.1	Multiple Spatial Vision of a Particular Object	226
10.5.2	Multiple Spatial Vision of the Whole Theatre	228
10.6	Europe-Related Missile Defense Scenario	229
10.6.1	Missile Defense Main Stages	229
10.6.2	Missile Defense Management in SGL	232

10.7	High-Level Battle Management in SGL . . . . .	233
10.7.1	Traditional Battle Management in BML . . . . .	233
10.7.2	Same Management Scenario in SGL . . . . .	235
10.8	Distributed Avionics . . . . .	237
10.9	Conclusion . . . . .	238
	References. . . . .	239
<b>11</b>	<b>Collective Robotics . . . . .</b>	<b>241</b>
11.1	Introduction . . . . .	241
11.2	Some Modern Robotic Examples . . . . .	242
11.2.1	Ground Robotics . . . . .	242
11.2.2	Aerial Robotics . . . . .	242
11.2.3	Maritime Robotics . . . . .	243
11.2.4	Collectively Behaving Robots . . . . .	244
11.2.5	General Demands to Advanced Robotic Systems . . . . .	245
11.3	Integration of Loose Swarming with Hierarchical Command and Control. . . . .	246
11.4	Multi-robot Hospital Service Example . . . . .	250
11.5	Exploration and Mapping of Unknown Distributed Space . . . . .	252
11.5.1	Different Mapping Scenarios . . . . .	253
11.5.2	Finding Optimal Route by the Created Free Space Grid. . . . .	256
11.6	Battling Forest Fires with Robotic Swarms. . . . .	257
11.7	Coastal Waters Cooperative Patrol . . . . .	259
11.8	Cooperative Finding of Oil Spill Center. . . . .	261
11.9	Maritime Massive Robotic Attack. . . . .	263
11.10	Swarm Against Swarm Aerial Scenario . . . . .	265
11.11	Cooperative Robotic Forestry and Agriculture . . . . .	266
11.12	Conclusion . . . . .	272
	References. . . . .	272
<b>12</b>	<b>Conclusions . . . . .</b>	<b>275</b>
12.1	General Advantages of the Technology Developed. . . . .	275
12.2	Contribution to the System Theory and Practice. . . . .	275
12.3	Some Particular Application Areas . . . . .	279
12.4	Implementation Issues and Future Plans . . . . .	282
	References. . . . .	282