

Control of *Living fish shoal* by mixing *Artificial agents*

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Background

Purpose & Current plan



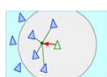
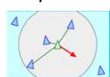
Collective animal behavior

The ordered collective behavior of groups is an emergent property arising from many decentralized individuals.

Is it possible to control the entire group via a few individuals?

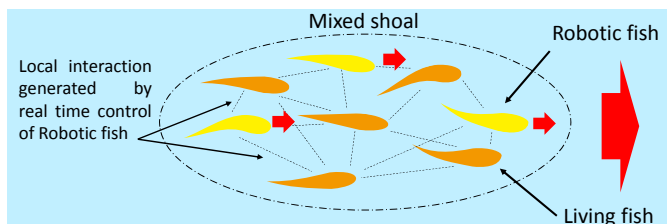
Model of group behavior – Boids (C. Reynolds, 1987)

The set of three rules governing local interaction,
1. Separation 2. Alignment 3. Cohesion,

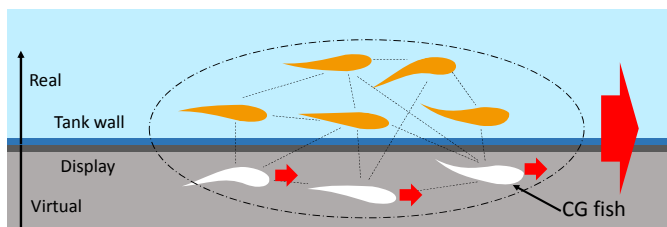


These rules generate highly collective behavior.

- Purpose: Control living fish shoal via Robotic fish



- First we are trialing CG fish instead of Robotic fish



Activity reports (Dec. 2013 ~ Mar. 2014)

Project start (Dec.)

- HWIP Okinawa Camp



Formed the team and made theme, "Control of fish shoal via artificial agents."

Research design (Jan.)

- Research survey
- Wiki for the project
- Target setting
- CG agent
- Explicit interaction between living fish and agents
- Real time control



- Medaka (*Oryzias latipes*)
Located at Humanware Lab.



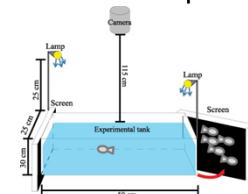
Arrangements of components (Feb.)

- CG animation
Following Boids algorithm

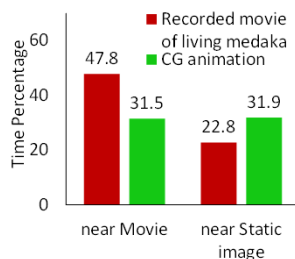


Trial experiment (Mar.)

- Trial of experiment



Two displays settled beside tank walls showing either actual Medaka movie or CG image of fish shoal. The tank was divided into three region and we recorded the time that fish spent near the moving CG fish compared with other areas.



Recorded movie of medaka shoal obviously attracted medaka, but our CG animation did not produce the same attraction. Anyway, we've done an experiment of fish behavior!

Next

- Improvement of CG animation
- Improved experimental design to better test our purpose