

**UNIVERSITI TEKNOLOGI MARA**

**VERIFICATION OF CORRECTNESS  
PROPERTIES FOR AGGREGATION  
BEHAVIOR OF SWARM ROBOTICS  
SYSTEM USING SPIN MODEL  
CHECKER**

**SITI SHAFINAZ BINTI ALI**

Dissertation submitted in fulfillment  
of the requirements for the degree of  
**Master of Science in Computer Networking**

**Faculty of Computer and Mathematical Sciences**

July 2015

## **ACKNOWLEDGEMENT**

First of all, I would like to express my gratitude to the all mighty, ALLAH S.W.T for the blessing, my parents and family members for their priceless support, encouragement, constant love, valuable advices and their understanding in completing this project. My special and heartily thanks to my supervisor, Encik Kamarul Ariffin Bin Abdul Basit who encouraged and directed me. I also would like to thanks to my dissertation coordinator, Dr. Nor Shahniza Binti Kamal Bashah in always assisting on the writing of this dissertation report.

I am also deeply thankful to my informants. Their names cannot be disclosed, but I want to acknowledge and appreciate their help and transparency during my dissertation. I also thank my family who encouraged me and prayed for me throughout the time of my research.

## Abstract

Swarm robotics is a new approach to the coordination of multi-robot systems which consist of large numbers of relatively simple robots (typically homogenous) which takes its inspiration from social insects. Referring previous research, the algorithm only focus on communication instead of rigorous checking. This research work focused on a developed swarm algorithm aimed at swarm aggregation. The main goal of this research is to verify the correctness properties of an existing model of aggregation behavior of swarm robotics. From the previous researcher, the aggregation algorithm based on the Probabilistic Finite State Automata (PFSA) is derived from the study of cockroach behavior. This algorithm is based on PFSA only relies on local interactions between individuals, the extensibility of the algorithm is very weak. In this research, we take inspiration from natural swarm and then transform to FSM. From FSM aggregation behavior algorithms is built for robot swarms. Model checking is a technique that was originally developed for verifying that finite state of the concurrent systems that implement specifications expressed in temporal logic. PROMELA language and verifying the proposed aggregation algorithm using the SPIN model checker. According to the result present in this research work, it has been proved that SPIN is capable to analyze the swarm robotic system using correctness properties. By verifying rigorously checking with SPIN model checker, the aggregation algorithm has been verified with no counter example and trustworthy.

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# CHAPTER 1

## INTRODUCTION

### 1.0 Introduction

This chapter explains the overview of the research work starting from the research background. Next is the problem statement which will be focusing and discussing according on the problem that related to this research work. Then scope and limitation and also significance of this research work will be explained.

#### 1.1.1 Background of study

A Swarm Robotics System is a special type of wide area and large-scale distributed system, which focuses on a group of robots cooperating to achieve the same goal as inspired by Swarm Intelligence. Swarm Robotics Systems are a kind of multi-robot systems which consist of many homogeneous autonomous robots without a global controller (T. Yasuda, N. Wada, K. Ohkura, and Y. Matsumura, 2013). Swarm Algorithm mostly inspired social behavior of insects and other animals. This is the concept of simple physical coordination allows the robot to cooperate to perform the duties.

Nature has solved this problem many times over. Schools of fish swim in unison, and are able to execute large scale collective manoeuvres to avoid a predator. Aggregation is a basic and most fundamental behavior for swarm robots because it enables robots to get closer and communicate to each other. By implementing it, the robots are able to perform other type of behaviors such as pattern formation, ‘task allocation’, ‘collective transport’ or ‘collective mapping’.

Termite colonies build large and very complex nests (complete with thermal regulation (Nicholas R, 2010). Ants collectively search a very large area and are capable of returning food to the nest. In each of these examples, there was no central leader with all the information making decisions for each individual. The origin of swarm robotics