

Ant Colony Optimization for Air Traffic Conflict Resolution

Nicolas Durand, Jean-Marc Alliot

DSNA/R&D/POM¹
<http://pom.tls.cena.fr/pom>

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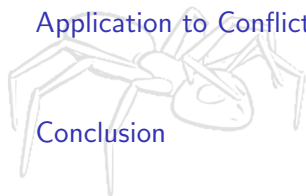
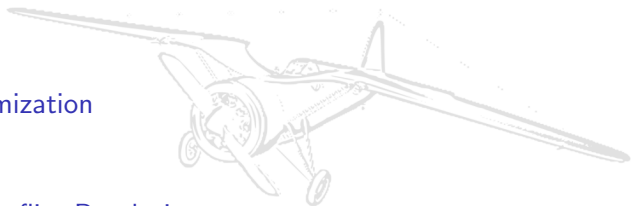


Introduction

Ant Colony Optimization

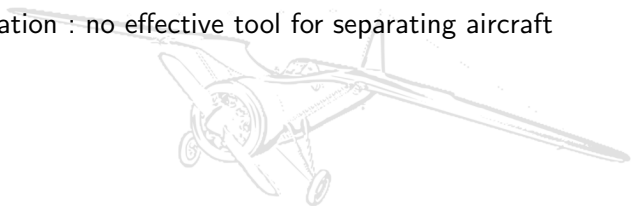
Application to Conflict Resolution

Conclusion



Conflict Resolution

- Current Situation : no effective tool for separating aircraft



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- New means : GPS capabilities (FMS enhancement), Data-Link communications \Rightarrow Enhance Trajectory Prediction



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 $\Rightarrow \frac{n(n-1)}{2}$ aircraft pairs $\Rightarrow 2^{\frac{n(n-1)}{2}}$ connected components to explore
- \Rightarrow Local optimization uneffective

Examples of existing algorithms

- Central & Global approaches
 - Integer Linear programming



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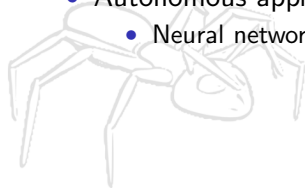
Examples of existing algorithms

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 - Integer Linear programming
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 - Branch and Bound Intervals
 - Genetic Algorithms
- Autonomous approaches



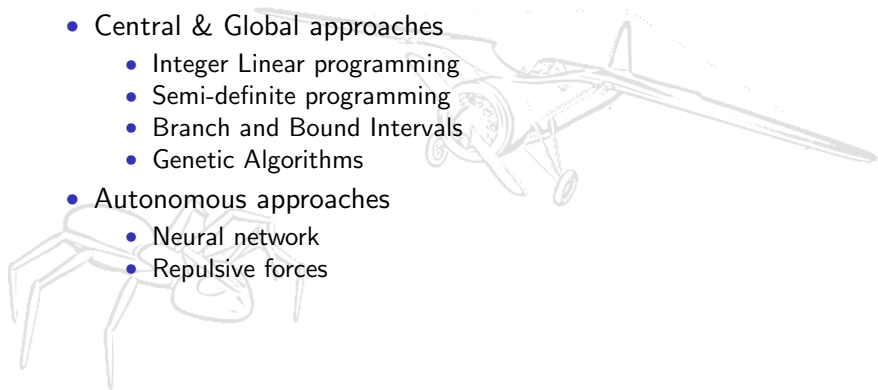
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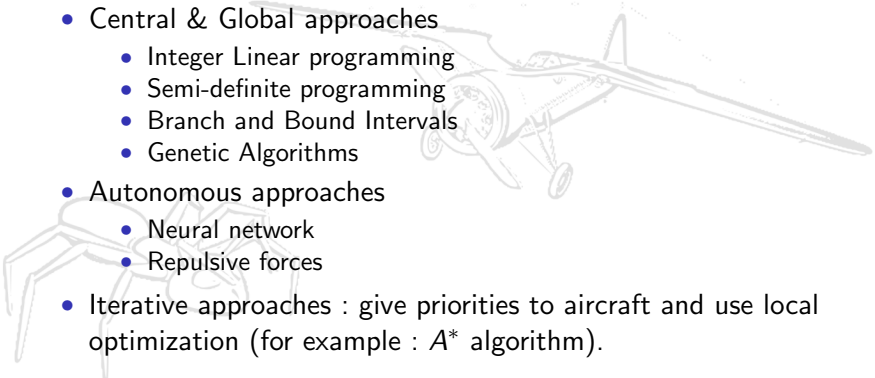


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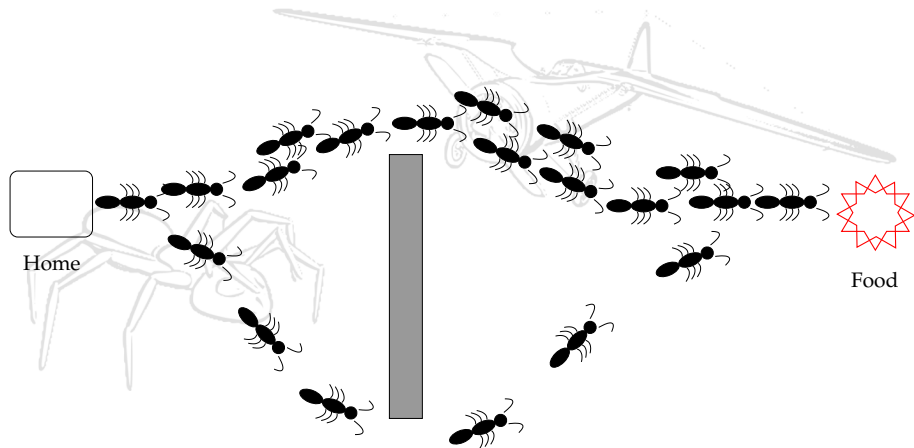


Examples of existing algorithms

- Central & Global approaches
 - Integer Linear programming
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 - Repulsive forces
 - Iterative approaches : give priorities to aircraft and use local optimization (for example : A^* algorithm).
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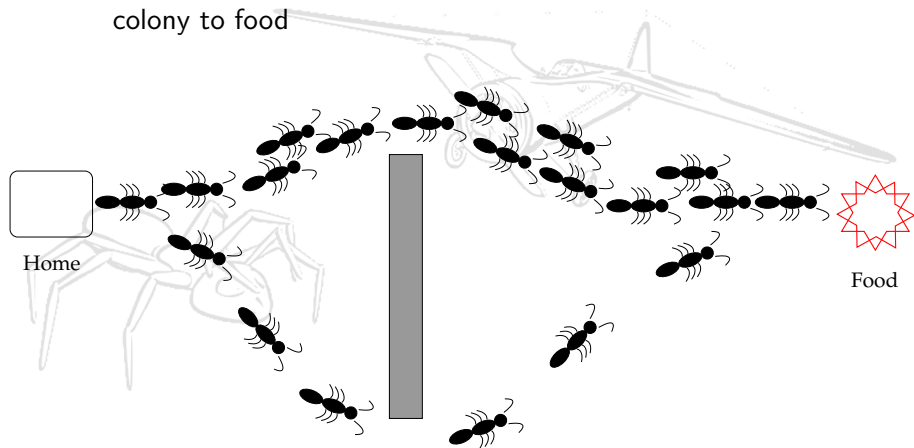
ACO principles

- Use the environment as a medium of communication



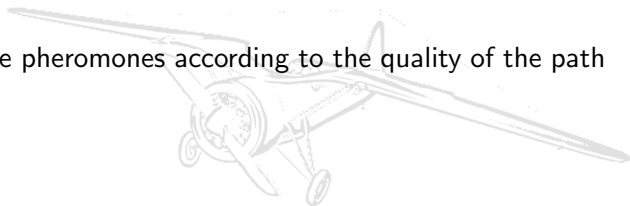
ACO principles

- Use the environment as a medium of communication
- Mimic the ants trying to find the shortest path from their colony to food



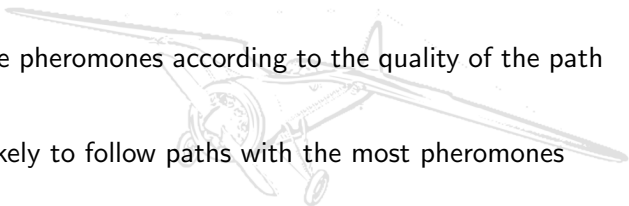
ACO algorithm principle

- Ants deposit pheromones according to the quality of the path they find



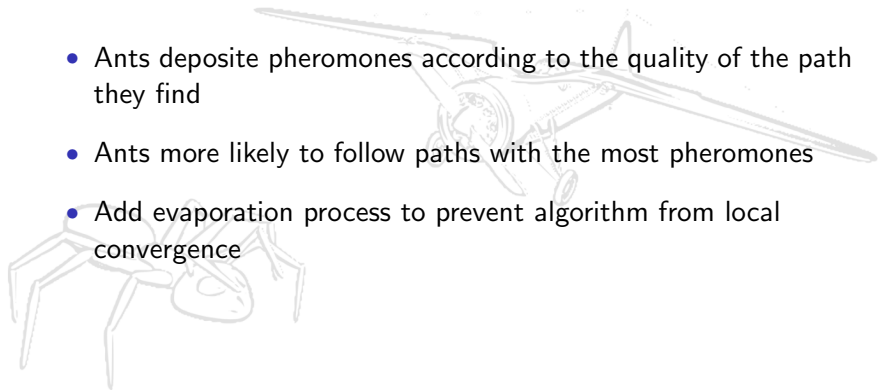
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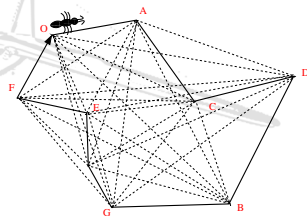


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- Stop when no more improvement

ACO for the Traveling Salesman Problem

- Ants sent on graph. Each ant builds complete path. Choice of next city influenced by pheromone quantity on paths.

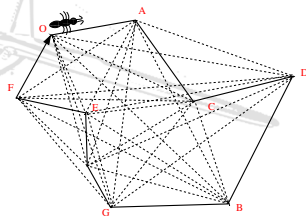


Vidéo

ACO for the Traveling Salesman Problem

- Ants sent on graph. Each ant builds complete path. Choice of next city influenced by pheromone quantity on paths.
- Ants deposite pheromones on the path

chosen :
$$\Delta\tau_{ij}(t) \propto \frac{1}{\sum L_{ij}}$$

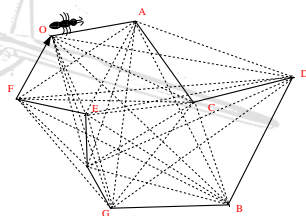


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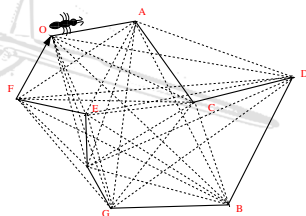
$$\tau_{ij} \leftarrow \rho \cdot \tau_{ij}$$



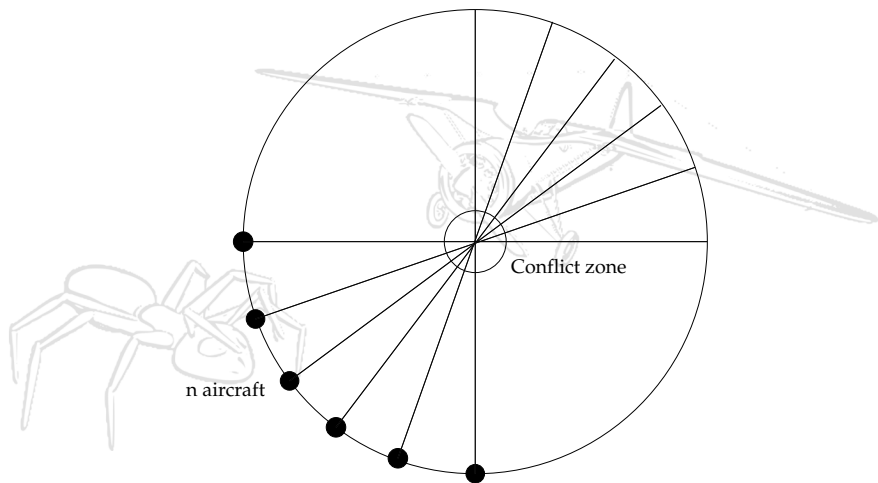
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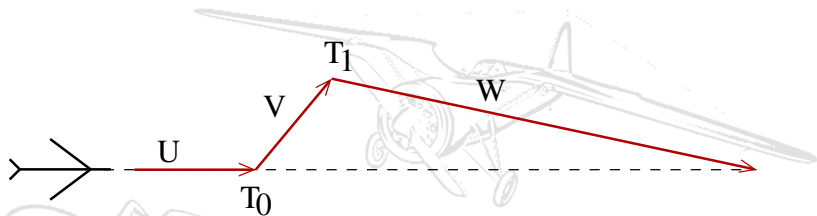
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[Vidéo](#)

n aircraft conflict example



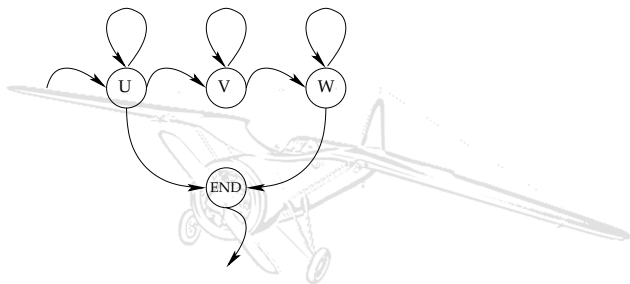
Maneuver modeling



Discretize time into *timesteps*

3 possible angles : 10, 20 or 30 degrees

Possible transitions



$$U_{i+1} = U_i$$

$$V_{i+1} = V_i + 6$$

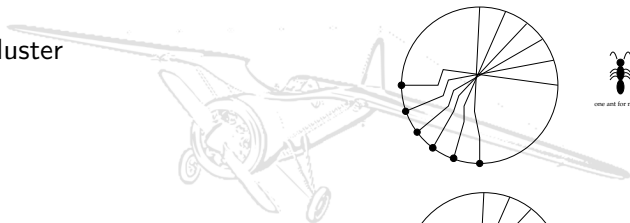
$$W_{i+1} = V_i$$

$$U_1 = 1, V_1 = 6 \text{ and } W_1 = 0$$

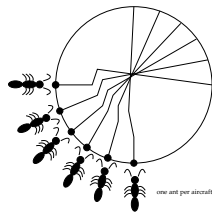
$$\text{Number of possible states at timestep } i = U_i + V_i + W_i = 12i - 5$$

One ant per cluster or one ant per aircraft

- one ant \rightarrow one cluster



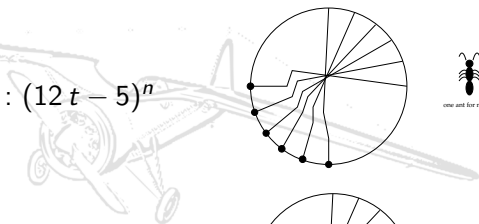
one ant for n aircraft



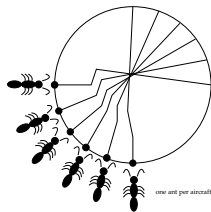
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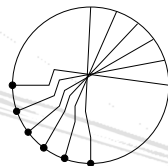
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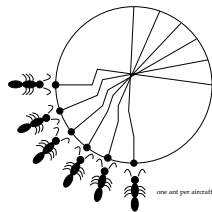
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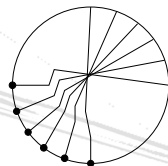
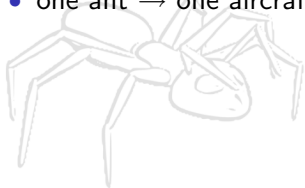
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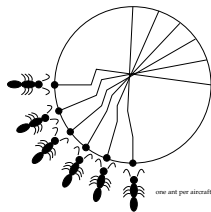
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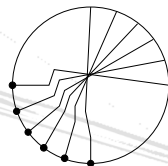
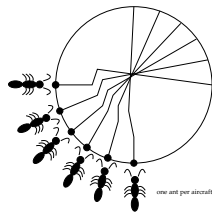
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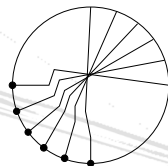
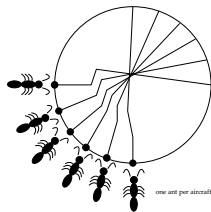
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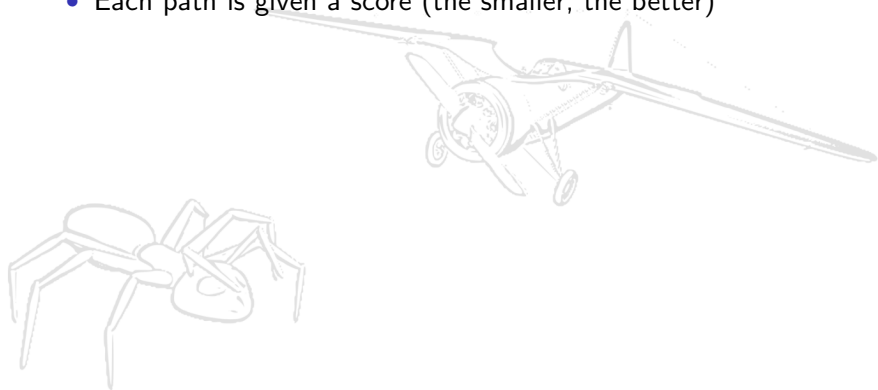
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- for n aircraft and t timesteps : $n(12t - 5)$ trails.
- For $n = 30$ and $t = 20$: more than 7050 trails instead of 10^{71}

one ant for n aircraft

one ant per aircraft

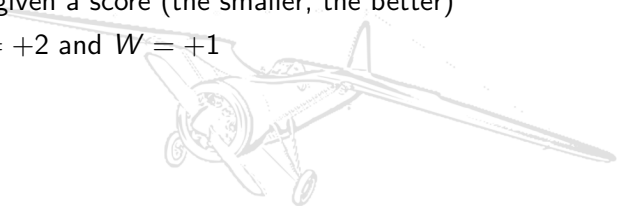
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where n_{out} is the number of "lost" ants, τ_0 the original quantity of pheromones, and s_{path} the score of the path followed by the ant.

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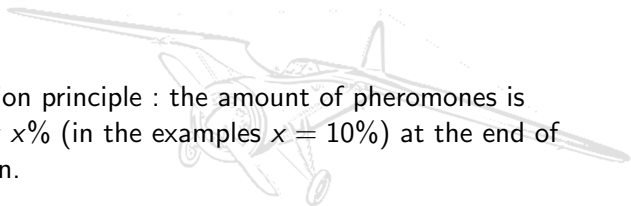
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- At each node, the next edge is chosen with a probability depending on its quantity of pheromones.

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- An evaporation principle : the amount of pheromones is decreased by $x\%$ (in the examples $x = 10\%$) at the end of each iteration.

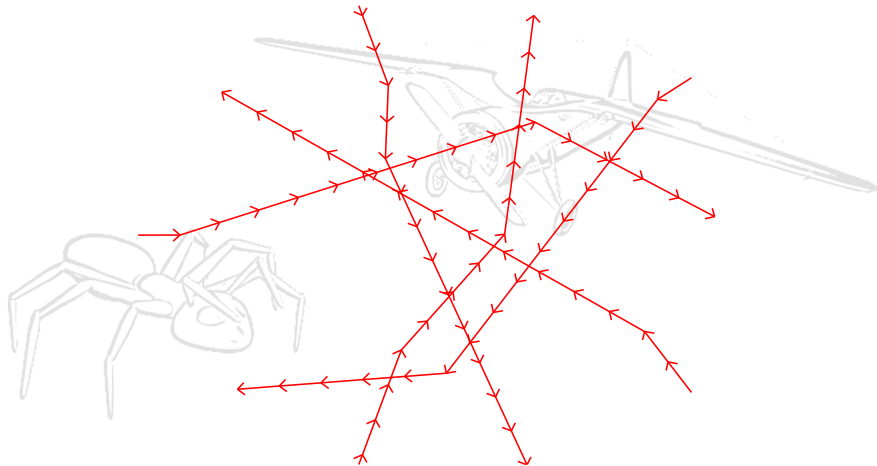


Algorithm description (2)

- An evaporation principle : the amount of pheromones is decreased by $x\%$ (in the examples $x = 10\%$) at the end of each iteration.
- Ending criteria : the score obtained by each bunch of ants no longer decreases.

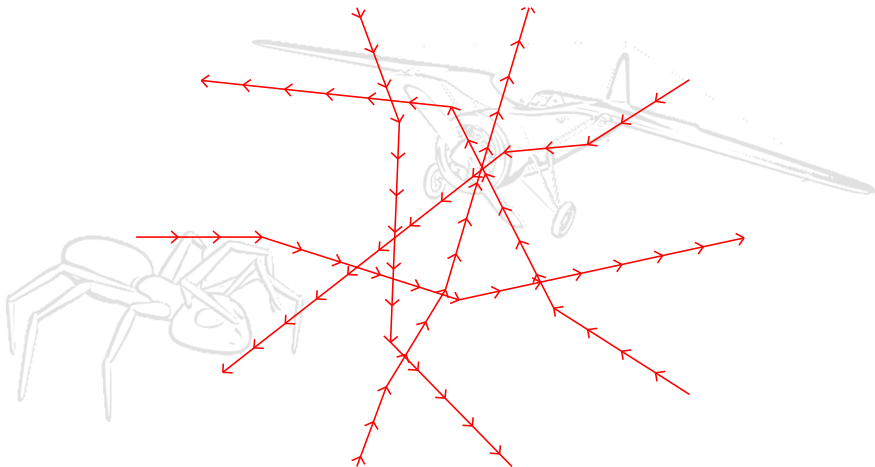
Example of 5 aircraft conflict resolution

18 iterations - score=89



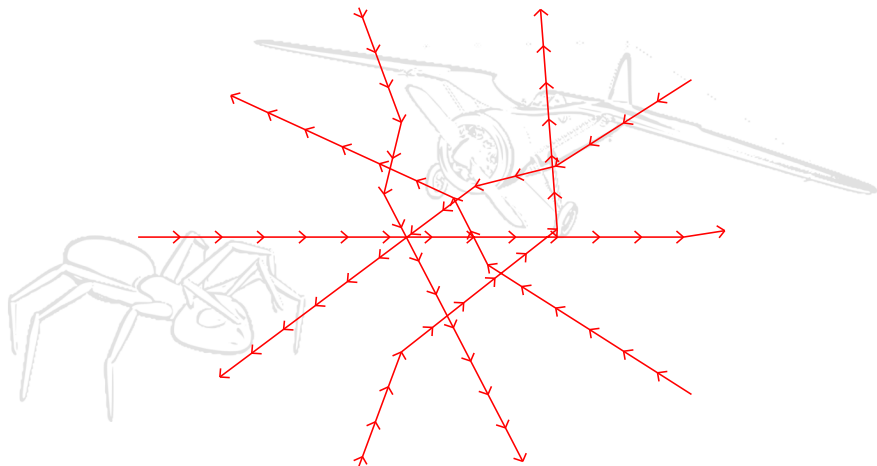
Example of 5 aircraft conflict resolution

46 iterations - score=78



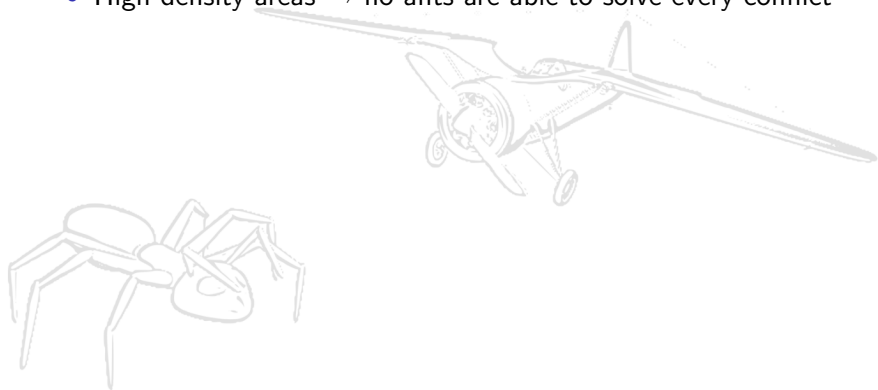
Example of 5 aircraft conflict resolution

105 iterations - score=50



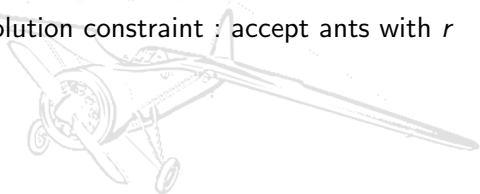
Algorithm improvement : constraint relaxation

- High density areas \rightarrow no ants are able to solve every conflict



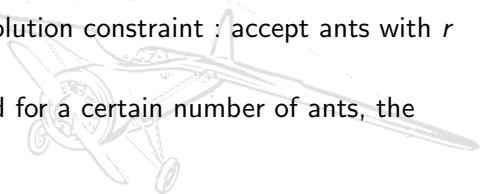
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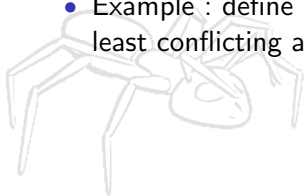
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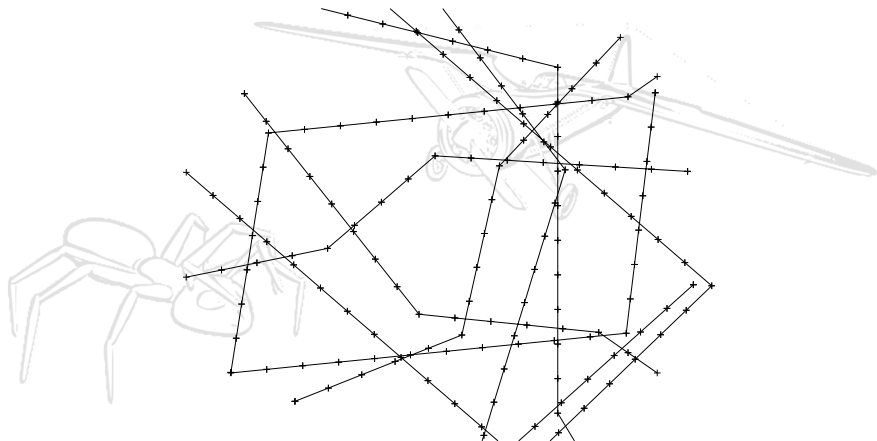
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- Example : define r as the minimum number of conflicts of the least conflicting ant
- r is the number of allowed conflicts per ant at the first generation.
- Reduce r when the number of ants having less than r conflicts is higher than $\frac{n}{r}$

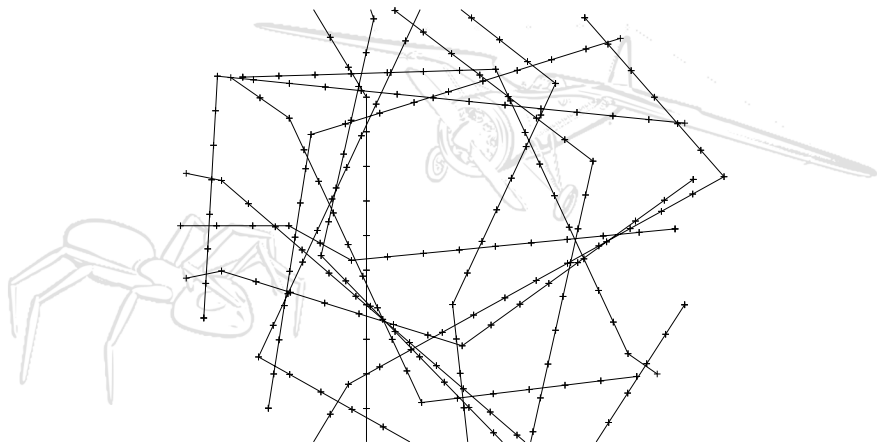
Example of 30 aircraft conflict resolution

generation: 0 - 4 conflicts max - 9 aircraft



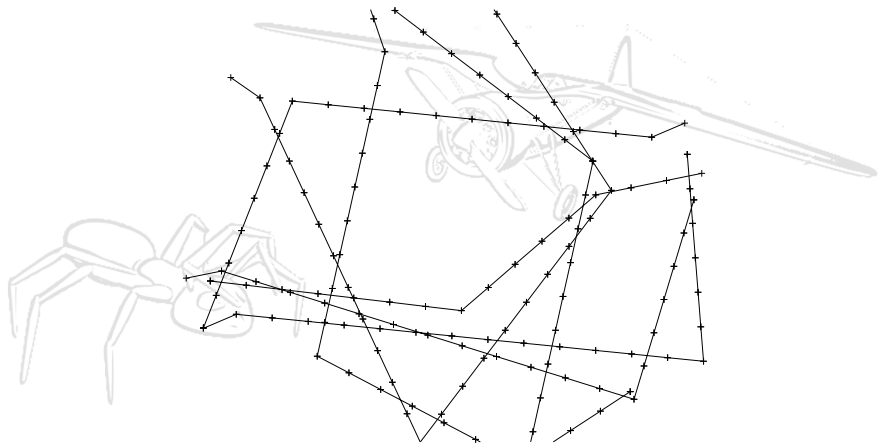
Example of 30 aircraft conflict resolution

generation: 14 - 3 conflicts max - 13 aircraft



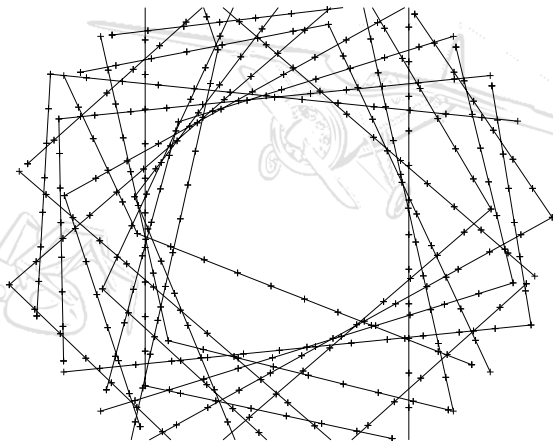
Example of 30 aircraft conflict resolution

generation: 15 - 2 conflicts max - 13 aircraft



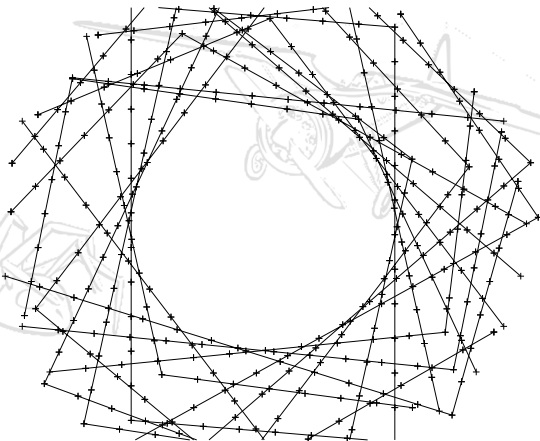
Example of 30 aircraft conflict resolution

generation: 44 - 2 conflicts max - 20 aircraft



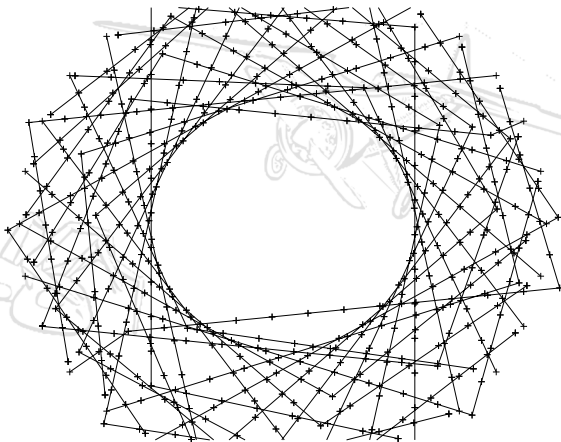
Example of 30 aircraft conflict resolution

generation: 45 - 1 conflict max - 20 aircraft



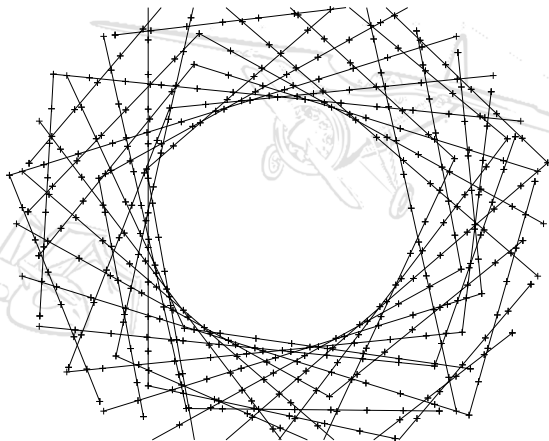
Example of 30 aircraft conflict resolution

generation: 47 - 1 conflict max - 30 aircraft



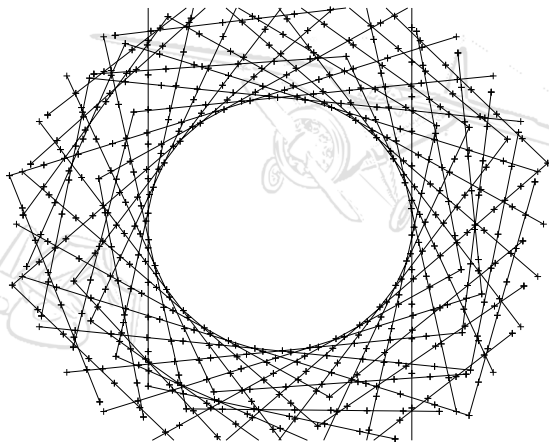
Example of 30 aircraft conflict resolution

generation: 48 - 0 conflict max - 30 aircraft



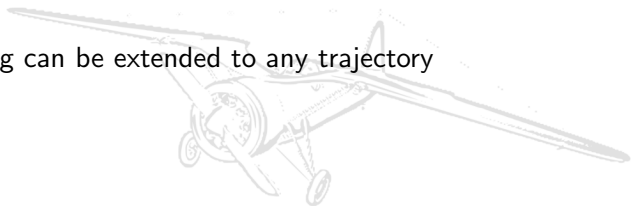
Example of 30 aircraft conflict resolution

generation: 65 - 0 conflict max - 30 aircraft



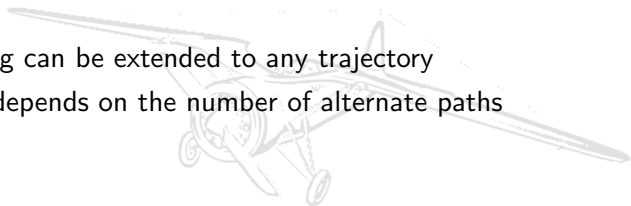
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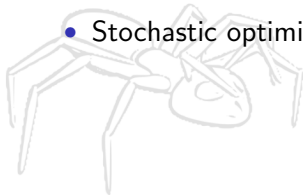
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- The modeling can be extended to any trajectory
- Complexity depends on the number of alternate paths available
- Results will be compared to the existing ERCS (using GAs)
- Stochastic optimization : no guarantee of solution or optimum
- No effective tool offered to controllers without significant enhancement of ground TP