

Biologically-inspired visual-motor coordination in a navigation problem

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www.framsticks.com

Details of this research are available in [JK06].

Framsticks

Introduction

Receptors
Brain
Behavior
Problem formulation

Biological inspiration

Optical illusions

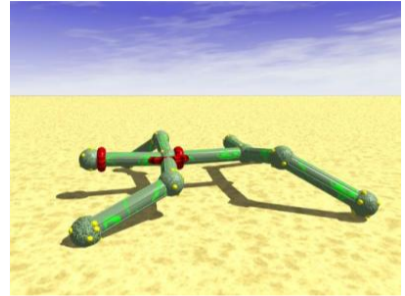
Solution

Image features
Feature aggregation
Architecture
Optimization

Summary

References

- three-dimensional life simulation environment
- physical structures (bodies) and control systems (brains) of creatures are modeled
- various kinds of experiments available, including simple optimization (by evolutionary algorithms), coevolution, open-ended and spontaneous evolution, distinct gene pools and populations, diverse genotype–phenotype mappings, and species and ecosystems modeling.



Framsticks' receptors

Introduction

Receptors

Brain

Behavior

Problem formulation

Biological inspiration

Optical illusions

Solution

Image features

Feature aggregation

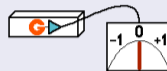
Architecture

Optimization

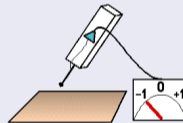
Summary

References

equilibrium



touch

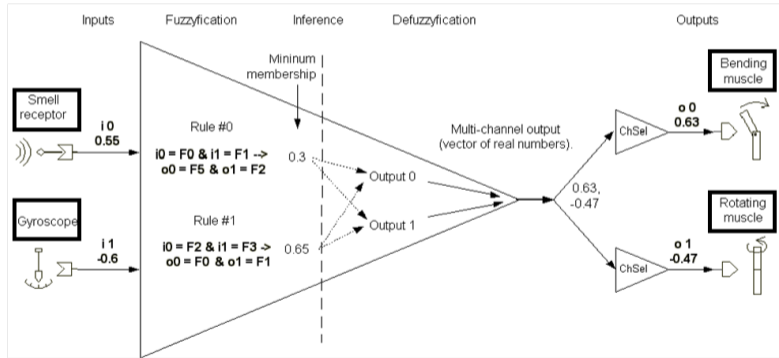


smell



Framsticks' "brains"

... can be composed of many neurons and many neuron types, including non-linear units, complex processing units, delay units, memory units, and even a fuzzy rule-based control system (shown below).



sensors

control system

efectors

Studying agents' behavior

Introduction

Receptors

Brain

Behavior

Problem formulation

Biological inspiration

Optical illusions

Solution

Image features

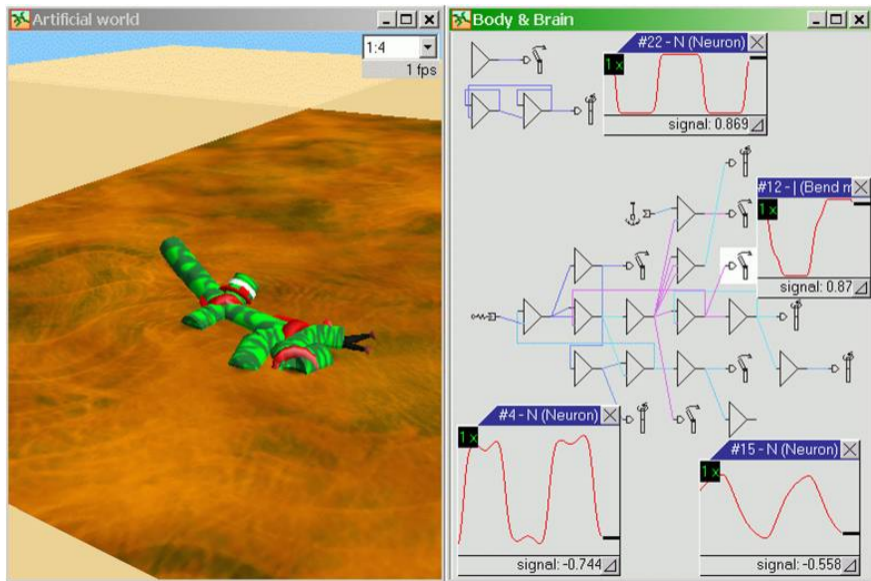
Feature aggregation

Architecture

Optimization

Summary

References



New Framsticks' sensor-effector module: visual-motor coordination module

Introduction

Receptors

Brain

Behavior

Problem formulation

Biological inspiration

Optical illusions

Solution

Image features

Feature aggregation

Architecture

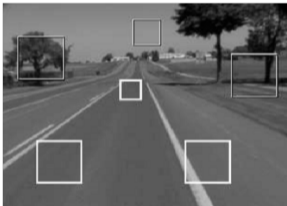
Optimization

Summary

References

The aim of the project:

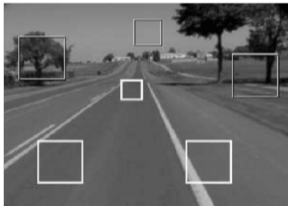
Design and implementation of the visual-motor coordination module in which motor actions, depending only on visual stimuli, solve some navigation tasks.



New Framsticks' sensor-effector module: visual-motor coordination module

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Introduction

Receptors

Brain

Behavior

Problem formulation

Biological inspiration

Optical illusions

Solution

Image features

Feature aggregation

Architecture

Optimization

Summary

References

New Framsticks' sensor-effector module: visual-motor coordination module

Introduction

Receptors

Brain

Behavior

Problem formulation

Biological inspiration

Optical illusions

Solution

Image features

Feature aggregation

Architecture

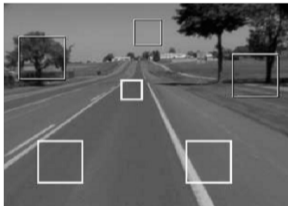
Optimization

Summary

References

The aim of the project:

Design and implementation of the visual-motor coordination module in which motor actions, depending only on visual stimuli, solve some navigation tasks.



New Framsticks' sensor-effector module: visual-motor coordination module

Introduction

Receptors

Brain

Behavior

Problem formulation

Biological inspiration

Optical illusions

Solution

Image features

Feature aggregation

Architecture

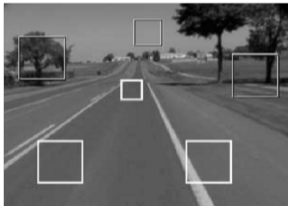
Optimization

Summary

References

The aim of the project:

Design and implementation of the visual-motor coordination module in which motor actions, depending only on visual stimuli, solve some navigation tasks.



To do list:

- 1 Definition of a navigation experiment with the success criterion
- 2 Design and implementation of the visual-motor coordination model
- 3 Tests – verification of the model

Navigation experiment

Introduction

Receptors
Brain
Behavior

Problem formulation

Biological inspiration

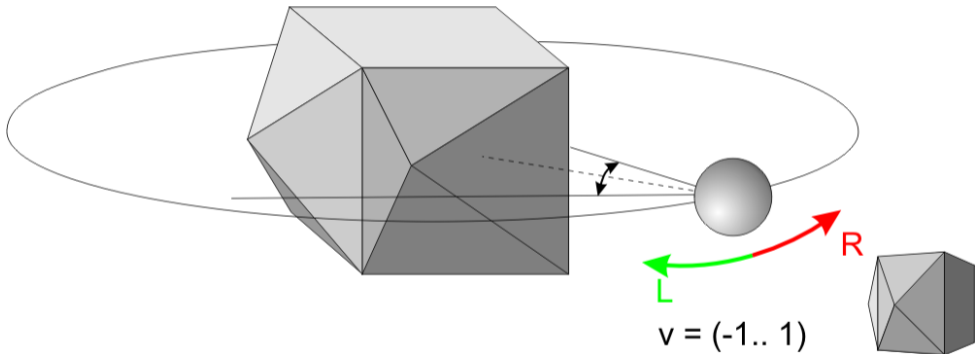
Optical illusions

Solution

Image features
Feature aggregation
Architecture
Optimization

Summary

References



“Life and death zones” navigation problem

Introduction

Receptors
Brain
Behavior

Problem formulation

Biological inspiration

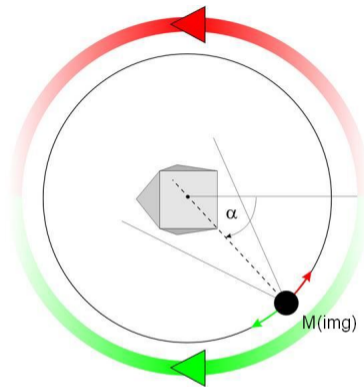
Optical illusions

Solution

Image features
Feature aggregation
Architecture
Optimization

Summary

References



$M(img)$ – movement speed $[-1, 1]$ based on visual stimulus img

Possible navigation solution of the “life and death zones” problem:

$$M(img) = \sin(\alpha)$$

Formal problem definition

Introduction

Receptors

Brain

Behavior

Problem formulation

Biological inspiration

Optical illusions

Solution

Image features

Feature aggregation

Architecture

Optimization

Summary

References

img_i – i -th image (its features) in a trip around the 3D object,
 $M(img_i)$ – expected value of movement velocity for img_i – e.g., $\sin(\alpha)$,
 $M'(img_i)$ – velocity output signal of the visual-motor coordination module.

Success measure = optimization function:

$$\min \sum_{i=0}^n |M(img_i) - M'(img_i)|$$

Architecture – data flow

Introduction

Receptors
Brain
Behavior

Problem formulation

Biological inspiration

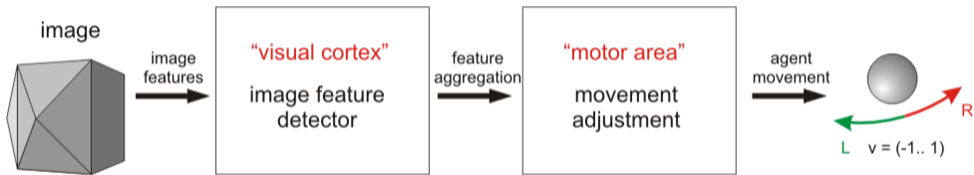
Optical illusions

Solution

Image features
Feature aggregation
Architecture
Optimization

Summary

References



visual-motor coordination module

Feature design – biological inspiration

Introduction

- Receptors
- Brain
- Behavior
- Problem formulation

Biological inspiration

- Optical illusions

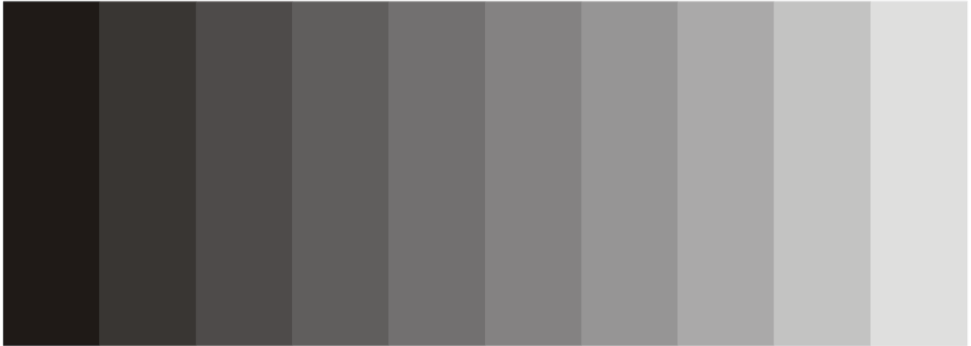
Solution

- Image features
- Feature aggregation
- Architecture
- Optimization

Summary

References

Mach bands:



All bars are uniformly colored, but each of them appear darker on the right side than on the left.

Hermann grid illusion

Introduction

Receptors

Brain

Behavior

Problem formulation

Biological inspiration

Optical illusions

Solution

Image features

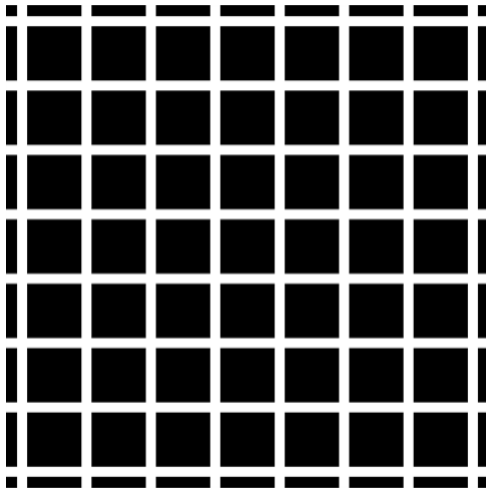
Feature aggregation

Architecture

Optimization

Summary

References



Dark patches appear in the street crossings, except the ones you are directly looking at.

Springer illusion

Introduction

Receptors
Brain
Behavior
Problem formulation

Biological inspiration

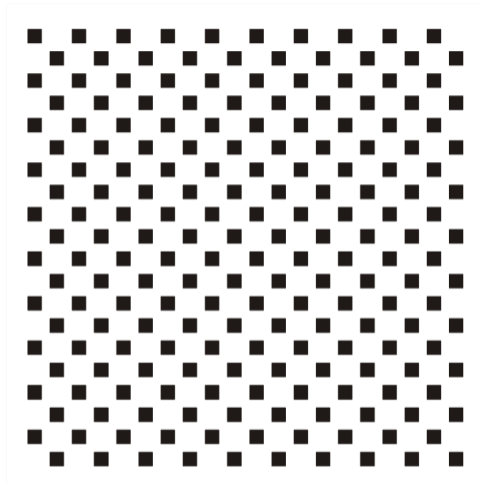
Optical illusions

Solution

Image features
Feature aggregation
Architecture
Optimization

Summary

References



The dot pattern can produce the perception of faint diagonal lines.

Explanation – lateral inhibition

Introduction

- Receptors
- Brain
- Behavior
- Problem formulation

Biological inspiration

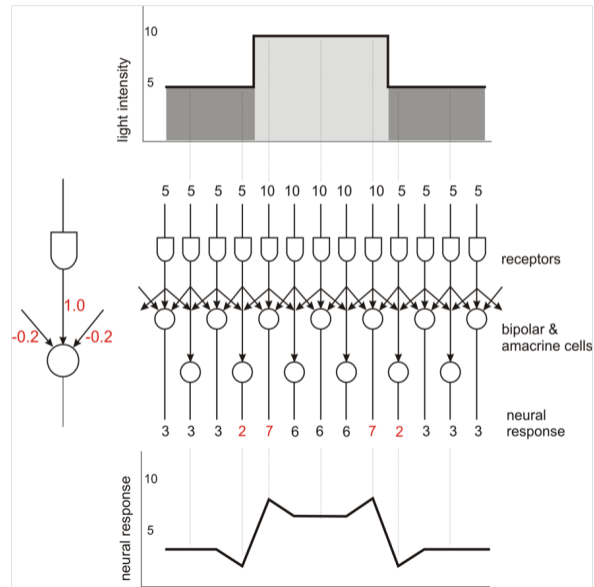
- Optical illusions

Solution

- Image features
- Feature aggregation
- Architecture
- Optimization

Summary

References



I-order visual cortex

Introduction

Receptors

Brain

Behavior

Problem formulation

Biological inspiration

Optical illusions

Solution

Image features

Feature aggregation

Architecture

Optimization

Summary

References

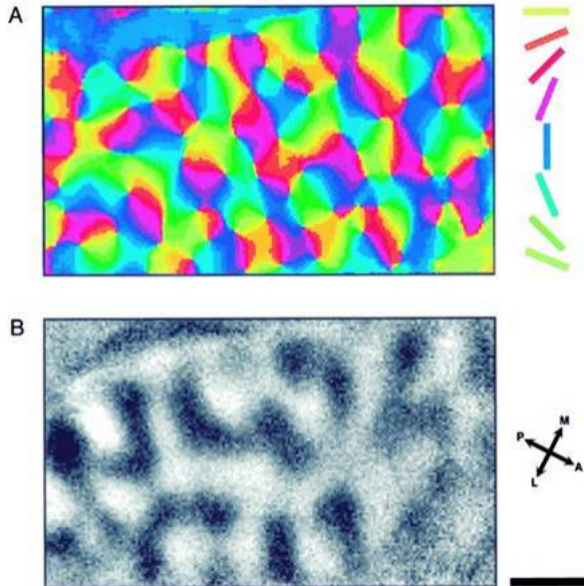


Image features – edge attributes

Introduction

Receptors

Brain

Behavior

Problem formulation

Biological inspiration

Optical illusions

Solution

Image features

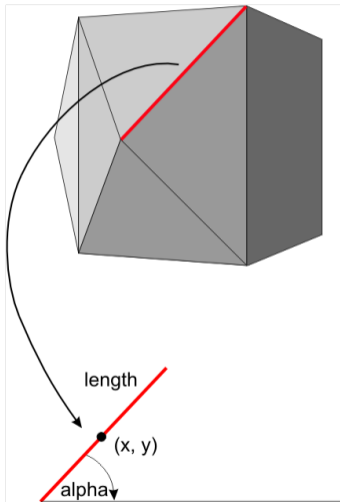
Feature aggregation

Architecture

Optimization

Summary

References



Problem – variable number of features

Introduction

Receptors
Brain
Behavior
Problem formulation

Biological inspiration

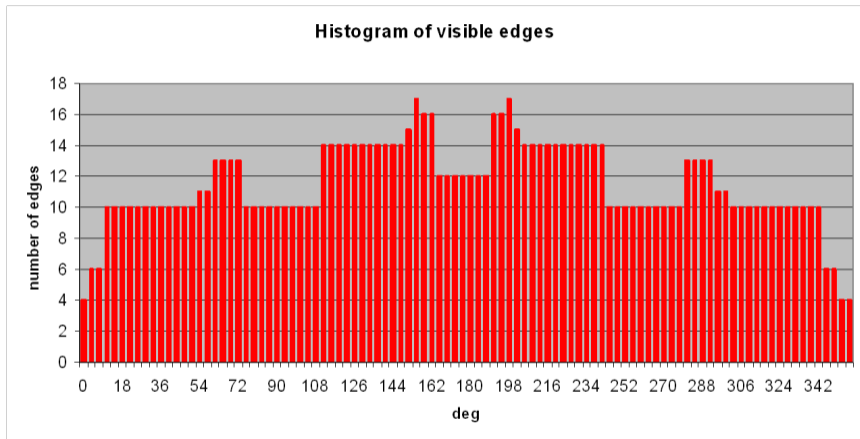
Optical illusions

Solution

Image features
Feature aggregation
Architecture
Optimization

Summary

References



Formal problem definition – continuation

Introduction

Receptors
Brain
Behavior
Problem formulation

Biological inspiration

Optical illusions

Solution

Image features
Feature aggregation
Architecture
Optimization

Summary

References

$$\min \sum_{i=0}^n |M(\text{img}_i) - M'(\text{img}_i)|$$

img_i – i -th image

$\text{img}_i \rightarrow V_i$ (feature extraction)

V_i – set of edges of the i -th image, each edge is described by 4 attributes ($x, y, \text{length}, \text{alpha}$).

$$v_i = M'(V_i)$$

Formal problem definition – continuation

Introduction

Receptors
Brain
Behavior
Problem formulation

Biological inspiration

Optical illusions

Solution

Image features
Feature aggregation
Architecture
Optimization

Summary

References

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img_i – i -th image

$img_i \rightarrow V_i$ (feature extraction)

V_i – set of edges of the i -th image, each edge is described by 4 attributes ($x, y, length, alpha$).

$$v_i = M'(V_i)$$

Problems:

- 1 Design of the parametric model M' , i.e., a parametric function which computes visual-motor coordination output (y_i) for any set of features (edges) – V_i .
- 2 Aggregation of features.

Feature aggregation – “fuzzy” sum of attributes

Introduction

Receptors
Brain
Behavior
Problem formulation

Biological inspiration

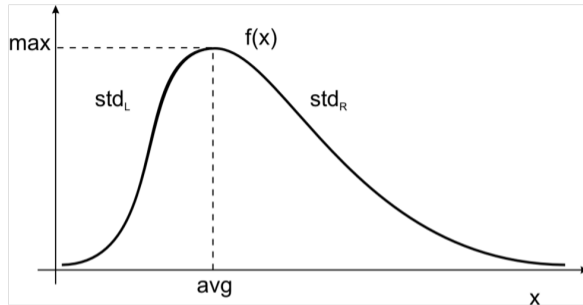
Optical illusions

Solution

Image features
Feature aggregation
Architecture
Optimization

Summary

References



$$v_i = M'(V_i)$$

$$V_i = \{A_j : A_j = \langle x_{i,j}, y_{i,j}, length_{i,j}, alpha_{i,j} \rangle\}$$

$$v_i = M' \left(\sum_j f_1(x_{i,j}), \sum_j f_2(y_{i,j}), \sum_j f_3(length_{i,j}), \sum_j f_4(alpha_{i,j}) \right)$$

The architecture of the motor area

Introduction

- Receptors
- Brain
- Behavior
- Problem formulation

Biological inspiration

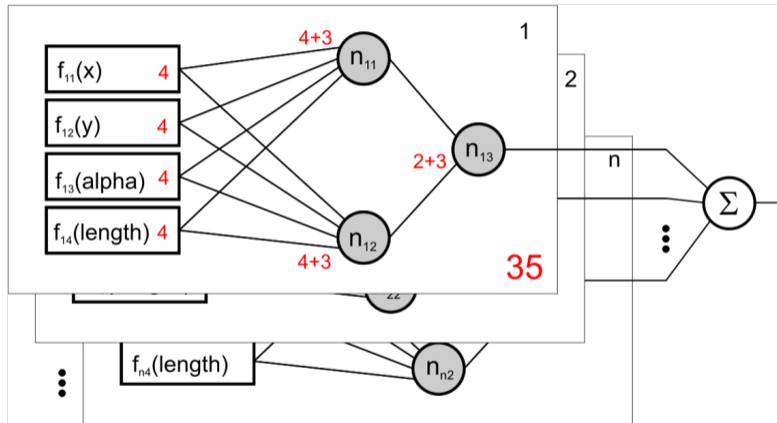
- Optical illusions

Solution

- Image features
- Feature aggregation
- Architecture
- Optimization

Summary

References



Optimization

Introduction

Receptors

Brain

Behavior

Problem formulation

Biological inspiration

Optical illusions

Solution

Image features

Feature aggregation

Architecture

Optimization

Summary

References

- variable step gradient optimization

Optimization

Introduction

Receptors

Brain

Behavior

Problem formulation

Biological inspiration

Optical illusions

Solution

Image features

Feature aggregation

Architecture

Optimization

Summary

References

- variable step gradient optimization

- optimization functions:

$$err = SUM(|M(o) - M'(o)|)$$

$$std = STD(M(o) - M'(o))$$

$$err + std$$

Optimization

Introduction

Receptors

Brain

Behavior

Problem formulation

Biological inspiration

Optical illusions

Solution

Image features

Feature aggregation

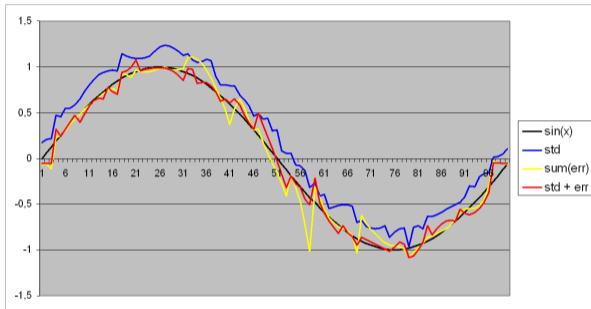
Architecture

Optimization

Summary

References

- variable step gradient optimization
- optimization functions:
 $err = SUM(|M(o) - M'(o)|)$
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 $err + std$



Optimization

Introduction

Receptors
Brain
Behavior
Problem formulation

Biological inspiration

Optical illusions

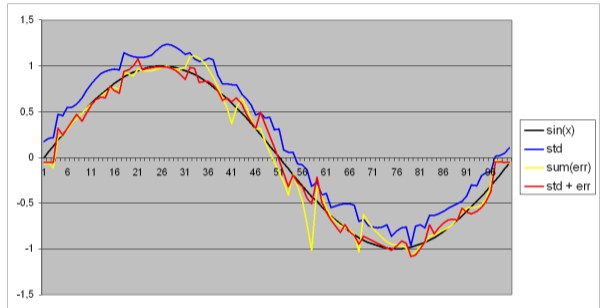
Solution

Image features
Feature aggregation
Architecture
Optimization

Summary

References

- variable step gradient optimization
- optimization functions:
 $err = SUM(|M(o) - M'(o)|)$
 $std = STD(M(o) - M'(o))$
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To do list – done:

- ✓ Definition of a navigation experiment with the success criterion
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- ✓ Tests – verification of the model

Introduction

Receptors
Brain
Behavior
Problem formulation

Biological inspiration

Optical illusions

Solution

Image features
Feature aggregation
Architecture
Optimization

Summary

References

https://www.framsticks.com/files/varia/VEye_sphere_navigation.png

https://www.framsticks.com/files/varia/VEye_gui.png

https://www.framsticks.com/files/varia/VEye_visual-motor_coordination.mp4

Summary

Introduction

Receptors
Brain
Behavior
Problem formulation

Biological inspiration

Optical illusions

Solution

Image features
Feature aggregation
Architecture
Optimization

Summary

References

- a new visual-motor coordination model has been proposed,
- biologically-inspired image features (edges) and a small set of their attributes (position – x, y ; *angle* and *length*) allow to successfully map high-level image information into low-level, single motor value (effector speed),
- the model has been successfully verified in “life & death zones” navigation tasks,
- additional experiments have proved generalization capability of the model – changing the size of the object and changing the distance of the agent from the object hardly increased error, so the system proved to be robust to minor changes in the environment,
- an interesting feature of the proposed model is that the system performance can be visualized and interpreted (explained) – it is possible to estimate the influence of each edge on the output value, and to visualize it.

Introduction

Receptors
Brain
Behavior
Problem formulation

Biological inspiration

Optical illusions

Solution

Image features
Feature aggregation
Architecture
Optimization

Summary

References

- experiments with unsupervised learning approach,
- implementation of better optimization techniques – metaheuristics,
- new navigation tasks in the 3D space,
- progression from simple S-R behavioral patterns toward more complex ones by the design and implementation of new cognition modules, which would lead to successful behaviors in more advanced and demanding tasks.

Introduction

- Receptors
- Brain
- Behavior
- Problem formulation

Biological inspiration

- Optical illusions

Solution

- Image features
- Feature aggregation
- Architecture
- Optimization

Summary

References

- [JK06] Jacek Jelonek and Maciej Komosinski. "Biologically-inspired Visual-motor Coordination Model in a Navigation Problem". In: *Knowledge-Based Intelligent Information and Engineering Systems*. Ed. by Bogdan Gabrys, Robert Howlett, and Lakhmi Jain. Vol. 4253. Lecture Notes in Computer Science. Berlin/Heidelberg: Springer, 2006, pp. 341–348. DOI: [10.1007/11893011_44](https://doi.org/10.1007/11893011_44). URL: <http://www.framsticks.com/files/common/BiologicallyInspiredVisualMotorCoordinationModel.pdf>.