

USING UNIFORM CROSSOVER TO REFINE SIMULATED ANNEALING SOLUTIONS FOR AUTOMATIC DESIGN OF SPATIAL LAYOUTS

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Keywords: Genetic algorithm, Simulated annealing, Hill-climbing, Cellular automata, Pedestrian simulation, Spatial layout.

Abstract: The ease of movement of people inside a public space is highly impacted by the public space layout itself. For example, the flow of a large number of people should be smooth in a well designed public space such as a stadium or hospital. In extreme cases, people might crush to death during emergency evacuations in poorly designed spaces. It is vital that design takes into account the smooth flow of pedestrians. In this paper we describe an initial exploration in using models of pedestrian flow combined with heuristic search to assist in the automatic design for spatial layout. A two-way pedestrian flow system is simulated and heuristic search techniques (genetic algorithm, simulated annealing and hill climbing) are used to find feasible spatial layouts based upon the generated statistics with promising results.

1 INTRODUCTION

Pedestrian flow is an integral part of spatial layout design. The spatial layout of public space has an enormous impact upon the ease with which people can move. There are a number of projects that have used pedestrian simulation to test pedestrian routes for airport terminal floor plans, stadium plans, shopping malls, and galleries (Batty et al., 2003, Dijkstra and Timmermans, 2002, Pan et al., 2006, Smedresman, 2006, Zhu et al., 2008). Based on the previous works, a computer simulation of pedestrian movement was identified as a useful method to help designers to understand the relation between spatial layout and human behaviour. It is vital that spatial layout design takes into account the smooth flow of pedestrians which will demonstrate how appropriate traffic control can effectively address congestion and safety issue. Pedestrian flow is going to be simulated by using the concept of cellular automata (CA). This approach is taken because CA presents a simple local rule describing the behaviour of each automaton that can create an approximation of actual individual behaviour (Dijkstra and Timmermans, 2002). Evolutionary algorithm search method is preferred for this study because of its principle of

artificial selection: the process involves randomly mutating a large number of individuals, ranking them, selecting the best, and iterating over and over again. According to Smedresman, 2006, they are particularly adept at sifting through large search space as in floor plan design domain to find solutions that may not intuitively present themselves.

Spatial layout is one of the most challenging phases of architectural design, and this type of problem is an NP-hard class which belongs to a complex combination optimization (Charman et al., 1994, Honda and Mizoguchi, 1995). In other words, algorithm for solving this problem needs a very long running time and a great storage space when the scale of the problem is large. For solving combinatorial optimization problem, effective methods include genetic algorithm, simulated annealing and hill climbing.

In this paper, we compare simulated annealing (SA) and hill climbing (HC) with updates that involve simple genetic algorithm (GA) operators in order to find solutions to a room layout. This involves walls/obstacles randomly distributed in a 10-by-10 grid with two types of pedestrian moving inside the space: one moving from left-to-right and

another one moving right-to-left based upon the cellular automata model of Yue et al., 2007. The aim of the experiments is to compare and understand how fast and effective the algorithms can generate (not simply refine as in Smedresman, 2006) automatic solutions to the spatial layout problem by using statistics generated from cellular automata pedestrian simulations.

2 METHODOLOGY

The experiments involve applying simulated annealing (SA), hill climbing (HC) and a form of repeated SA that is updated with genetic algorithm (GA) operator (SA-GAO) to solve the spatial layout problem. It is not feasible to have a full GA implementation due to the very complex fitness function involving several pedestrian simulations. The methods analysed in this paper have been run using a pedestrian movement model developed by Yue et al., 2007. They proposed two pedestrian movement models on a square lattice for small system based on cellular automata (CA), i.e. two-way pedestrian flow and four-way pedestrian flow. They introduced a technique to simplify tactically the process into the interaction of four dynamic parameters, which can reflect the pedestrian judgment on the surrounding conditions and decide the pedestrian's choice of action such as moving ahead, stopping to wait, position exchange, lane switching, back stepping, etc. In this paper, the two-way pedestrian flow system is simulated and studied using the Dynamic Parameters Model from Yue et al., 2007 to consider direction split and pedestrians' walking preference.

In this model, pedestrian choose to wait or move according to the corresponding transition payoff based on four parameters:

- *Direction-parameter* indicates the cell's degree of approximation to the pedestrian destination;
- *Empty-parameter* indicates whether the cell is occupied or empty;
- *Forward-parameter* describes the proportion of empty cells in the field ahead of his or her target position;
- *Category-parameter* describes the proportion of the number of empty cells and pedestrians homogenous with the subject in his or her direction of destination in the field around his or her target position.

2.1 Hill Climb and Simulated Annealing

The pseudocode for our implementation of this approach is listed in Figure 1.

```

Input: Number of iterations, iteration,
and a random starting layout, startrep,
starting temperature, temperature

    oldrep = startrep;

    Apply 10 pedestrian simulations to
    generate statistics, stats

    fit = fitness(stats)

    bestfit = fit

    for loop = 1:iteration

        rep=oldrep;
        Apply move operator to rep

        Apply 10 pedestrian simulations to
        stats

        newfit = fitness(stats);

        dscore = newfit-fit

        if ((bestfit < newfit) OR
        (rand(0,1) < e(dscore/temperature))

            bestfit = newfit

            oldrep = rep;

        else

            rep = oldrep;

        end if

        temperature = temperature*0.9

    end for

Output: rep
    
```

Figure 1: Pseudo-code for the Hill Climb and Simulated Annealing.

In order to set this as a HC, the starting temperature is set to zero. Note that the fitness here

uses the statistics generated from 10 repeated runs of the CA pedestrian simulation. This is done to ensure that one simulation does not result in a ‘lucky’ fitness score for one layout based upon the starting positions of the pedestrians.

2.2 Move Operator

The move operator, shown in Figure 2, takes into account the size of the simulation grid and randomly moves one object a fraction of this distance (determined by the parameter *changedegree*). The result of the move is then checked to see if the new coordinates are within the bounds of the grid and do not result in the object overlapping with others. The operator is defined fully in Figure 2, where *unidrnd(min,max)* is a uniform discrete random number generator with limits of *min* and *max*.

```

Input: Size of simulation grid, W, size of object, sizeobj, current x-coordinate, oldx, current y-coordinate, oldy

Set the degree of change to make based upon a fraction of the grid size:
    changedegree=W/2;

Choose a random object in the grid, i

    [oldx,oldy] = current x and y coordinates of object i

    xchange = unidrnd(-changedegree/2, changedegree/2)

    ychange = unidrnd(-changedegree/2, changedegree/2)

if ( (oldy+ychange) and (oldx + xchange) is within grid boundary AND new object position does not overlap another object taking into account sizeobj)

    newx=oldx+xchange;

    newy=oldy+ychange;

    end if

Move object i to position [newx, newy]

Output: newx, newy
    
```

Figure 2: Pseudo-code for Move Operator.

2.3 Fitness Function

The fitness function is calculated based on the statistics that are generated using the pedestrian simulation. The statistics take the form of a 3x3 matrix, *leftstats*, representing the sum of decisions for left-moving pedestrians and a similar decision matrix for right-moving pedestrians, *rightstats*. Therefore, the middle cell in each grid represents how many times the pedestrians decided to stay in the same cell as last time. As we wish to encourage free flow we wish to increase the fitness for layouts that results in many cases of left moving pedestrians moving left and right moving pedestrians moving right, whilst penalising the fitness of any decisions where the left-moving pedestrians move right and vice-versa. For example, consider the two *stats* matrices for left and right pedestrians. It is clear that the *leftstats* reflect a ‘good’ result as the pedestrians have generally moved in the desired direction more often whereas for *rightstats* this is not the case.

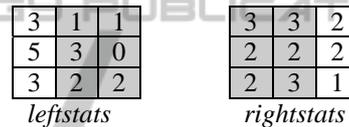


Figure 3: Left and Right statistics – describe as 3x3 matrix.

In general, we wish to maximise the first column in *leftstats* and the third column in *rightstats* whilst minimising the other statistics (shaded in the example, Figure 3). Therefore, we use the following fitness function:

$$rightfitness = \text{sum}(rightstats(3,1:3)) - \text{sum}(rightstats(1,1:3))$$

$$leftfitness = \text{sum}(leftstats(1,1:3)) - \text{sum}(leftstats(3,1:3))$$

$$fitness = rightfitness + leftfitness$$

Higher fitnesses should reflect simulations whereby pedestrians have moved in the direction that they wish more often.

2.4 SA Genetic Algorithm Operators

We extend our work by using GA-style operators. A full GA implementation is not feasible due to the very complex fitness function involving several pedestrian simulations. Therefore, we extend our work by using GA-style operators on the results of multiple starts of SA. The initial ‘parents’ are selected from the best (selection are made based on more consistent fitnesses value with a good final layout which is 9.000 or above) solutions generated

from a number of SA experiments. We experimented with different style of combination for two ‘parents’ that more or less act like uniform crossover. In the crossover operation, two new children are formed by exchanging the genetic information between two ‘parent’ chromosomes. Multipoint crossover defines crossover points as places between loci where an individual can be split. Uniform crossover generalizes this scheme to make every locus a potential crossover point. A crossover mask, the same length as the individual structure is created at random and the parity of the bits in the mask indicate which parent will supply the offspring with which bits.

Consider the following two parents with 10 binary variables each:

Parent1 1 1 1 1 1 1 1 1 1 1
 Parent2 2 2 2 2 2 2 2 2 2 2

For each variable, the parent who contributes its variable to the children is chosen randomly with equal probability. Here, children 1 is produced by taking the bit from parent 1 if the corresponding mask bit is 1 or the bit from parent 2 if the corresponding mask bit is 2. Children 2 is created using the inverse of the mask, usually.

Mapping 1 2 1 1 2 2 2 1 1 2

After crossover the new individuals are created:

Children1 1 2 1 1 2 2 2 1 1 2
 Children2 2 1 2 2 1 1 1 2 2 1

3 RESULTS

The experiments involved running HC, SA and SA-GAO on the problem of trying to arrange 10 pre-defined objects in a 10x10 grid with 5 ‘left’ pedestrians and 5 ‘right’ pedestrians. Each algorithm was run 10 times and the learning curves were inspected. The final fitnesses and quality of the layouts were then investigated. Finally, some inspection of sample simulations on the final layouts was carried out to look for interesting characteristics.

3.1 Summary Statistics

Table 1: Summary statistics of final fitness.

Method	Min.	Max.	Mean	Std. Dev.
SA1	3.846	9.790	7.615	1.854
SA2	4.786	9.938	8.085	1.477
HC	6.992	9.276	8.586	0.724

Table 1 shows the minimum, maximum and mean values for the final fitness of each algorithm over ten experiments, where SA1 represent SA with initial temperature of 1.0 and SA2 represents a temperature of 0.2. The statistical values of HC show the robustness of the solutions with the standard deviation of 0.724. The standard deviation is relatively low, which indicates that HC is among the most consistent approach in finding a good solution (the mean is also higher). However, the maximum value is less than SA2 indicating that the SA can sometimes escape some of the local optima.

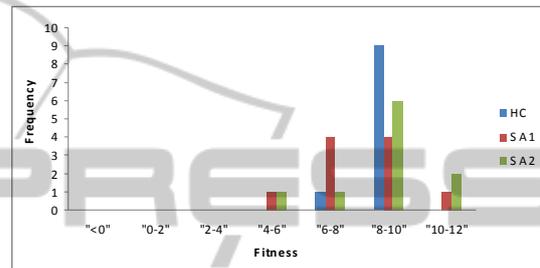


Figure 4: Distribution of Final Fitness for each Search Method.

Figure 4 shows the final fitness distribution for each search method. From Table 1 and this figure, it is clear that the distribution of the fitnesses for the SA algorithms for both temperatures is spread more than for the HC. SA is sometimes empirically better at avoiding local minima than hill-climbing though HC is the most consistent approach based on Table 1.

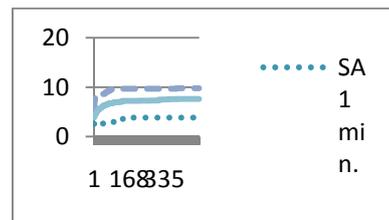


Figure 5: Max, Min and Mean learning curves for SA temperature = 1.0.

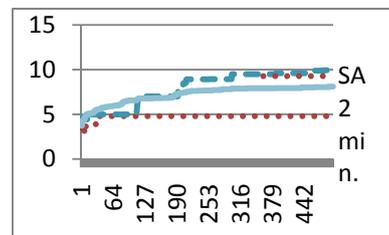


Figure 6: Max, Min and Mean learning curves for SA temperature = 0.2.

The graphs in Figures 5 and 6 show the best, worst and mean learning curves for the SA algorithm over 10 reruns with two initial starting temperatures. The total iteration for every learning curve is 500 iterations. These curves characterise the typical SA with noisy search at high temperatures in the early phases followed by smoother learning in the later stages. It seems the higher starting temperatures result in more diverse final fitnesses. This could be due to the fact that the fitness landscape is very noisy and difficult to negotiate, resulting in many local optima.

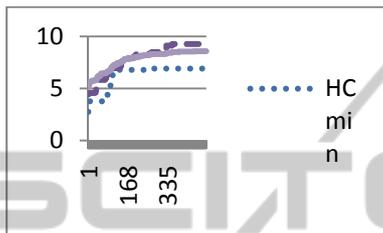


Figure 7: Max, Min and Mean learning curves for HC.

However, the HC curves in Figure 7 show far less variations in final fitness that is surprising. Despite the mean final fitness of HC being better than SA, it is clear that the SA does indeed escape sub-optimal local peaks in the fitness on some occasions with the maximum final fitness being higher than HC. Clearly this is likely to be due to HC techniques exploiting the best available solution for possible improvement but neglecting exploring a large portion of the search space (Michalewicz & Fogel, 2000). Additionally, the higher starting temperature for SA seems to result in better solutions but at the expense of greater variance in the final fitness.

We then expanded our work to SA-GAO. Four different mappings were run and each was run 10 times. Seven ‘parents’ were selected from the consistent resulting solutions of previous SA experiments where each of their fitness values is 9.000 or above. The highest ‘parent’ fitness is 10.048 as shows in Table 2.

Table 2: Selected ‘parents’ and their fitness value for SA-GAO experiments.

Parents	Fitness
Parent1	9.382
Parent2	10.048
Parent3	9.010
Parent4	9.124
Parent5	9.780
Parent6	9.438
Parent7	9.414

Table 3: ‘Children’ with highest fitness values generated from SA-GAO of four different combinations.

Mapping	Max. Fitness
1122211222	10.434
1112221112	10.460
1112111211	10.398
1212121212	9.672

Table 3 shows different mappings of uniform crossover and the highest fitness value of the children for each combination. The fitnesses of the ‘children’ scored better compared to the ‘parents’ highest fitness value. This implies that recombining the best of the SA solutions can indeed improve the overall layout without having to implement a full GA which would not be feasible for such an expensive fitness function.

Table 4: ‘Children’ with highest fitness values generated from SA-GAO of one hundred random combinations.

Mapping	Max. Fitness
2122112111	9.642
2212221212	Child1: 9.714, Child2: 9.476
1211122122	9.178
2121221121	9.846
2121122212	9.322
2221121212	9.092
2212211112	9.656
2122112111	9.466
1121111221	9.046
2122211111	9.200
2122222111	9.378
1222211122	9.112

We next tried to experiment with one hundred random combination of mappings. The highest fitness of the children is 9.846 as shown in Table 4 generated from ‘2121221121’ mapping. Note that mapping ‘2212221212’ generates both ‘child1’ and ‘child2’ with good fitness (higher than 9.000). This result shows that it may be necessary to run quite a large number of recombination of parents to ensure improved fitness. It may also imply that further mutations are required to fine-tune these new solutions.

3.2 Exploring the Final Layouts

We now explore some of the characteristics of the final layouts discovered by the algorithms. The blue/down arrows in figure 8 (a)-(e) represent the final positions of wall layout; 500 iterations using SA, HC and SA-GAO algorithm. Meanwhile, the black and pink arrows represented left and right pedestrians moving in each ways. From Figure 8 (a)

and (b), we can see clearly that the bad layouts are generated from the series of lowest fitness. The higher the fitness, the better the layout as in Figure 8 (c), (d) and (e). Notice in 8 (a) (the lowest fitness for SA with starting temperature of 0.2) the large wall created by the objects on the right were blocking any left-right movement. It may be that more complex operators are required to escape from this point. The lowest scoring HC in Figure 8 (b) features a long wide corridor in the centre which results in an

“almost dead end” at the left. Notice the completed “corridor” in Figure 8 (c) from left to right with a width of 1 cell allowing free flow of both left and right pedestrians. Also note the alternative routes. Figure 8 (d) shows the highest scoring layout of HC with the existence of single cell corridors allowing some free flowing movements. Finally, notice in the Figure 8 (e) for the highest fitness of SA-GAO that there are two “corridors” at the top and bottom of the final layout.

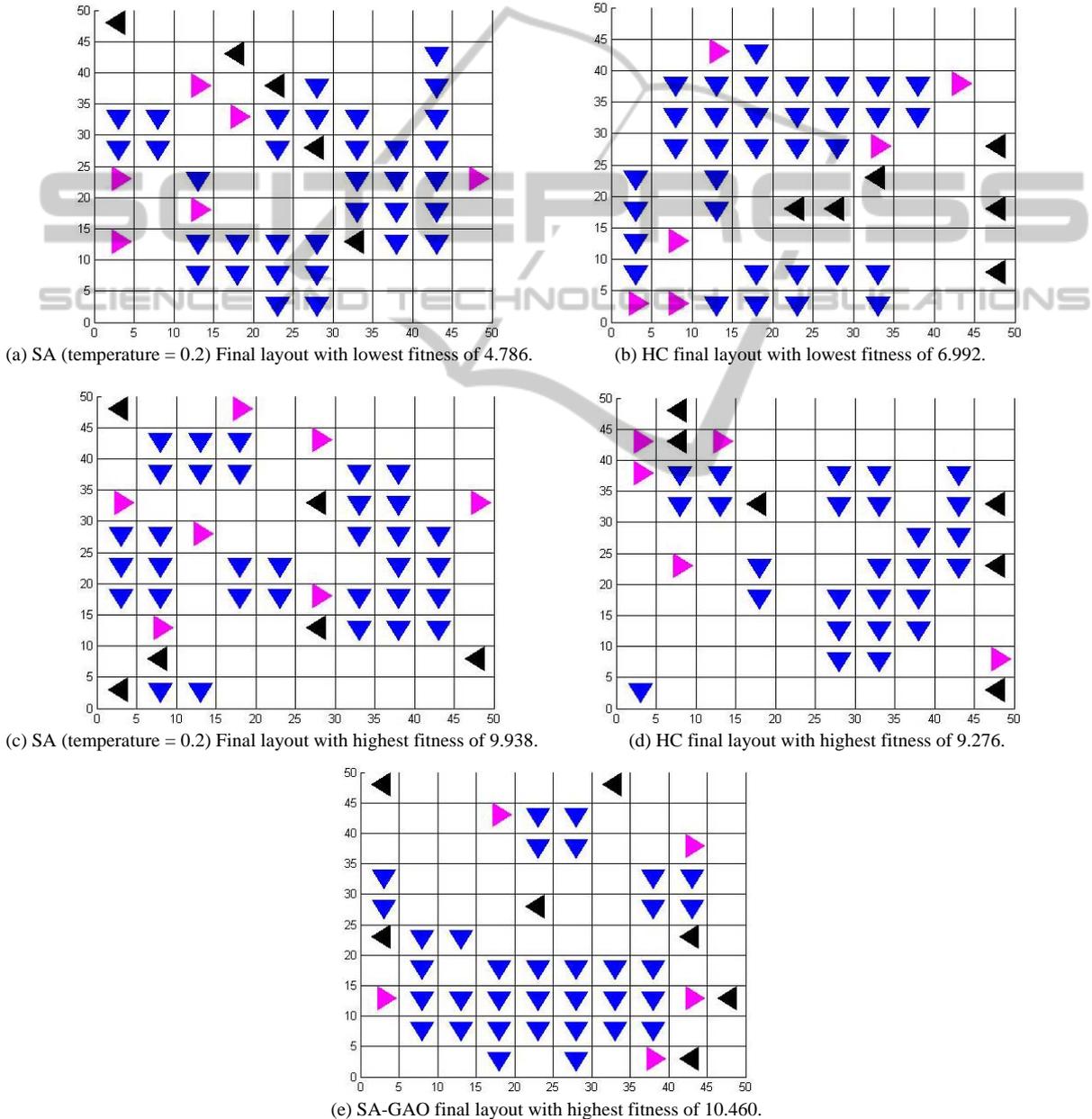


Figure 8: (a)-(e). SA, HC and SA-GAO final layouts.

4 CONCLUSIONS

In this paper we explored using pedestrian flow simulations combined with heuristic search to assist in the automatic design for spatial layout planning. Using pedestrian simulations, the activity of crowds can be used to study the consequences of different spatial layouts.

Based on the results that have been observed in this paper, we have demonstrated that simple heuristic searches appear to deal with the NP-hard spatial layout design problem to some degree, at least on the very much simplified problem addressed here. Both SA and HC are able to automatically find adequate solutions to this problem when incorporated with the pedestrian simulator. Moreover, the solution is further improved when we paired 'parents' and apply a GA style operator using our method SA-GAO. Whilst it is not guaranteed that the optimal solution will be found, this does not mean that useful and unexpected designs cannot be learnt using these types of approaches. Indeed, the real positive outcome of the experiments here is that we found certain characteristics that may not have been immediately expected. We have found several key results:

- The highest fitnesses produced useful layouts, passageways (diagonal or horizontal) and clustered objects. These demonstrably show smoother flow when running the simulations and exploring the statistics of movement;
- SA has more variations in final fitness. Whilst HC cannot 'escape' local optima, SA does sometimes manage to do this with better final solutions. In general, the distribution of final fitnesses is higher for SA though more adventurous solutions are explored;
- SA-GAO generated better solutions compared to SA solutions: the SA-GAO children show higher fitnesses than their parents. This implies that solutions with lower fitnesses may still offer useful information and when these are recombined in a constructive way, they generate better overall layouts than if no recombination is used.

We feel that approaches that combine heuristic search with simulation should offer the ability to find novel design solutions in more complex design layouts with larger spaces, more objects, different constraints and different pedestrian goals. In general, we found that SA-GAO treats combinations of two existing solutions as being 'near', making the 'children' share the properties of their parents, so

that a child of two good solutions is more probably good than a random solution as in HC and SA.

Future work will involve extending our work by make use of real world data to validate the discovered layouts. We have access to large amounts of pedestrian flow data in existing public buildings and private offices. We will use the data to further test our algorithms on layouts discovered from more complex real-world spaces.

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