

Package ‘DatabionicSwarm’

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Type Package

Title Swarm Intelligence for Self-Organized Clustering

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Description Algorithms implementing populations of agents that interact with one another and sense their environment may exhibit emergent behavior such as self-organization and swarm intelligence. Here, a swarm system called databionic swarm (DBS) is introduced. DBS is able to adapt itself to structures of high-dimensional data such as natural clusters characterized by distance and/or density based structures in the data space. The first module is the parameter-free projection method called Pswarm (Pswarm()), which exploits the concepts of self-organization and emergence, game theory, swarm intelligence and symmetry considerations. The second module is the parameter-free high-dimensional data visualization technique, which generates projected points on the topographic map with hypsometric tints defined by the generalized U-matrix (GeneratePswarmVisualization()). The third module is the clustering method itself with non-critical parameters (DBSclustering()). Clustering can be verified by the visualization and vice versa. The term DBS refers to the method as a whole. It enables even a non-professional in the field of data mining to apply its algorithms for visualization and/or clustering to data sets with completely different structures drawn from diverse research fields. The package is based on the book of Thrun, M.C.: “Projection Based Clustering through Self-Organization and Swarm Intelligence” (2018) <DOI:10.1007/978-3-658-20540-9>. A comparison to 26 common clustering algorithms on 15 datasets is presented on the website.

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Imports Rcpp, deldir, GeneralizedUmatrix

Suggests DataVisualizations, knitr (>= 1.12), rmarkdown (>= 0.9), rglwidget, plotrix, geometry, sp, spdep, AdaptGauss, ABCanalysis, parallel, matrixStats, rgl, png, ProjectionBasedClustering, parallelDist, pracma

LinkingTo Rcpp, RcppArmadillo

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LazyData TRUE

URL <http://www.deepbionics.org>

Encoding UTF-8

VignetteBuilder knitr

BugReports <https://github.com/Mthrun/DatabionicSwarm/issues>

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Repository CRAN

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 DatabionicSwarm-package

Swarm Intelligence for Self-Organized Clustering

Description

Algorithms implementing populations of agents that interact with one another and sense their environment may exhibit emergent behavior such as self-organization and swarm intelligence. Here, a swarm system called databionic swarm (DBS) is introduced. DBS is able to adapt itself to structures of high-dimensional data such as natural clusters characterized by distance and/or density based structures in the data space. The first module is the parameter-free projection method called Pswarm (Pswarm()), which exploits the concepts of self-organization and emergence, game theory, swarm intelligence and symmetry considerations. The second module is the parameter-free high-dimensional data visualization technique, which generates projected points on the topographic map with hypsometric tints defined by the generalized U-matrix (GeneratePswarmVisualization()). The third module is the clustering method itself with non-critical parameters (DBSclustering()). Clustering can be verified by the visualization and vice versa. The term DBS refers to the method as a whole. It enables even a non-professional in the field of data mining to apply its algorithms for visualization and/or clustering to data sets with completely different structures drawn from diverse research fields. The package is based on the book of Thrun, M.C.: "Projection Based Clustering through Self-Organization and Swarm Intelligence" (2018) <DOI:10.1007/978-3-658-20540-9>. A comparison to 26 common clustering algorithms on 15 datasets is presented on the website.

Details

For a brief introduction to **DatabionicSwarm** please see the vignette [Short Intro to the Databionic Swarm \(DBS\)](#).

Package: Databionic swarm
 Type: Package
 Version: 1.1.0
 Date: 2018-07-02
 License: CC BY-NC-SA 4.0

Index of help topics:

| | |
|-----------------------------|--|
| ClusteringAccuracy | ClusteringAccuracy |
| DBSclustering | Databionic swarm clustering (DBS) |
| DatabionicSwarm-package | Swarm Intelligence for Self-Organized Clustering |
| DefaultColorSequence | Default color sequence for plots |
| Delaunay4Points | Adjacency matrix of the delaunay graph for BestMatches of Points |
| DelaunayClassificationError | Delaunay Classification Error (DCE) |

| | |
|-----------------------------------|---|
| Delta3DWeightsC | Intern function |
| DijkstraSSSP | Internal function: Dijkstra SSSP |
| GeneratePswarmVisualization | Generates the Umatrix for Pswarm algorithm |
| Hepta | Hepta form FCPS |
| Lsun3D | Lsun3D inspired by FCPS |
| ProjectedPoints2Grid | Transforms ProjectedPoints to a grid |
| Pswarm | A Swarm of Databots based on polar coordinates (Polar Swarm). |
| PswarmCurrentRadiusC2botsPositive | intern function, do not use yourself |
| RelativeDifference | Relative Difference |
| RobustNormalization | RobustNormalization |
| ShortestGraphPathsC | Shortest GraphPaths = geodesic distances |
| findPossiblePositionsCsingle | Intern function, do not use yourself |
| getCartesianCoordinates | Intern function: Transformation of Databot indizes to coordinates |
| getUmatrix4Projection | depricated! see GeneralizedUmatrix() Generalisierte U-Matrix fuer Projektionsverfahren |
| plotSwarm | Intern function for plotting during the Pswarm annealing process |
| rDistanceToroidCsingle | Intern function for 'Pswarm' |
| sESOM4BMUs | Intern function: Simplified Emergent Self-Organizing Map |
| setGridSize | Sets the grid size for the Pswarm algorithm |
| setPolarGrid | Intern function: Sets the polar grid |
| setRmin | Intern function: Estimates the minimal radius for the Databot scent |
| setdiffMatrix | setdiffMatrix shortens Matrix2Curt by those rows that are in both matrices. |
| trainstepC | Internal function for sESOM |

Further information is available in the following vignettes:

DatabionicSwarm Short Intro to the Databionic Swarm (DBS) (source, pdf)

Note

For interactive Island Generation of a generalized Umatrix see interactiveGeneralizedUmatrixIsland function in the package **ProjectionBasedClustering**.

If you want to verify your clustering result externally, you can use Heatmap or SilhouettePlot of the CRAN package **DataVisualizations**.

Author(s)

Michal Thrun

Maintainer: Michael Thrun <m.thrun@gmx.net>

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

[Ultsch/Thrun, 2017] Ultsch, A., & Thrun, M. C.: Credible Visualizations for Planar Projections, in Cottrell, M. (Ed.), 12th International Workshop on Self-Organizing Maps and Learning Vector Quantization, Clustering and Data Visualization (WSOM), IEEE Xplore, France, 2017.

[Thrun et al., 2016] Thrun, M. C., Lerch, F., Loetsch, J., & Ultsch, A.: Visualization and 3D Printing of Multivariate Data of Biomarkers, in Skala, V. (Ed.), International Conference in Central Europe on Computer Graphics, Visualization and Computer Vision (WSCG), Vol. 24, Plzen, <http://wscg.zcu.cz/wscg2016/short/A43-full.pdf>, 2016.

Successfully applied in

[Thrun, 2018] Thrun, M. C. : Cluster Analysis of the World Gross-Domestic Product Based on Emergent Self-Organization of a Swarm, in Papiez, M. & Smiech, S. (eds.), Proc. 12th Professor Aleksander Zelias International Conference on Modelling and Forecasting of Socio-Economic Phenomena, pp. 523-532, Foundation of the Cracow University of Economics, Cracow, Poland, 2018.

[Thrun et al., 2018] Thrun, M. C., Breuer, L., & Ultsch, A. : Knowledge discovery from low-frequency stream nitrate concentrations: hydrology and biology contributions, Proc. European Conference on Data Analysis (ECDA), pp. accepted, Paderborn, Germany, 2018.

[Weyer-Menkhoﬀ et al., 2018] Weyer-Menkhoﬀ, I., Thrun, M. C., & Loetsch, J.: Machine-learned analysis of quantitative sensory testing responses to noxious cold stimulation in healthy subjects, European Journal of Pain, Vol. 22(5), pp. 862-874, DOI: 10.1002/ejp.1173, 2018.

[Kringel et al., 2018] Kringel, D., Geisslinger, G., Resch, E., Oertel, B. G., Thrun, M. C., Heine- mann, S., & Loetsch, J. : Machine-learned analysis of the association of next-generation sequencing based human TRPV1 and TRPA1 genotypes with the sensitivity to heat stimuli and topically applied capsaicin, Pain, in press, doi 10.1097/j.pain.0000000000001222, 2018

Examples

```
data('Lsun3D')
##2d projection, without instant visualization of steps
#DistanceMatrix hast to be defined by the user.
InputDistances=as.matrix(dist(Lsun3D$Data))

projection=Pswarm(InputDistances)
#2d projection, with instant visualization
#of steps and DataMatrix (Distance is Euclidean per default)

projection=Pswarm(Lsun3D$Data,Cls=Lsun3D$Cls,PlotIt=T)
#
##Computation of Generalized Umatrix
```

```

# If Non Euclidean Distances are used, Please Use \code{SammonsMapping}
# from the ProjectionBasedClustering package with the correct OutputDimension
# to generate a new DataMatrix from the distances (see SheppardDiagram
# or KruskalStress)
visualization=GeneratePswarmVisualization(Data = Lsun3D$Data,

projection$ProjectedPoints,projection$LC)
## Visualizuation of GeneralizedUmatrix,
# Estimation of the Number of Clusters=Number of valleys
library(GeneralizedUmatrix)#install if not installed
GeneralizedUmatrix::plotTopographicMap(visualization$Umatrix,visualization$Bestmatches)
## Automatic Clustering
# number of Cluster from dendrogram (PlotIt=TRUE) or visualization
Cls=DBScustering(k=3, Lsun3D$Data,

visualization$Bestmatches, visualization$LC,PlotIt=FALSE)
# Verification, often its better to mark Outliers manually

GeneralizedUmatrix::plotTopographicMap(visualization$Umatrix,visualization$Bestmatches,Cls)

## Not run:
# To generate the 3D landscape in the shape of an island
# from the toroidal topograpic map visualization
# you may cut your island interactivly around high mountain ranges
Imx = ProjectionBasedClustering::interactiveGeneralizedUmatrixIsland(visualization$Umatrix,
visualization$Bestmatches,Cls)

GeneralizedUmatrix::plotTopographicMap(visualization$Umatrix,
visualization$Bestmatches, Cls=Cls,Imx = Imx)

## End(Not run)
## Not run:
library(ProjectionBasedClustering)#install if not installed
Cls2=ProjectionBasedClustering::interactiveClustering(visualization$Umatrix,
visualization$Bestmatches, Cls)

## End(Not run)

```

ClusteringAccuracy *ClusteringAccuracy*

Description

ClusteringAccuracy

Usage

ClusteringAccuracy(PriorCls,CurrentCls,K=9)

Arguments

PriorCls
CurrentCls clustering result
K Maximal number of classes for computation.

Details

Here, accuracy is defined as the normalized sum over all true positive labeled data points of a clustering algorithm. The best of all permutation of labels with the highest accuracy is selected in every trial because algorithms arbitrarily define the labels.

Value

Accuracy Between zero and one

Author(s)

Michael Thrun

References

Michael C. Thrun, Felix Pape, Alfred Ultsch: Benchmarking Cluster Analysis Methods in the Case of Distance and Density-based Structures Defined by a Prior Classification Using PDE-Optimized Violin Plots, ECDA, Potsdam, 2018

Examples

```
data(Hepta)

InputDistances=as.matrix(dist(Hepta$Data))
projection=Pswarm(InputDistances)
visualization=GeneratePswarmVisualization(Data = Hepta$Data,

projection$ProjectedPoints,projection$LC)
Cls=DBScustering(k=7, Hepta$Data, visualization$Bestmatches,

visualization$LC,PlotIt=FALSE)
ClusteringAccuracy(Hepta$Cls,Cls,K=9)
```

 DBSclustering

Databonic swarm clustering (DBS)

Description

Automated Clustering approach of the Databonic swarm with abstract U distances, which are the geodesic distances based on high-dimensional distances combined with low dimensional graph paths by using ShortestGraphPathsC.

Usage

```
DBSclustering(k, DataOrDistance, BestMatches, LC, StructureType = TRUE, PlotIt = FALSE,
              method = "euclidean",...)
```

Arguments

| | |
|----------------|---|
| k | number of clusters, how many to you see in the topographic map (3D landscape)? |
| DataOrDistance | Either [1:n,1:d] Matrix of Data (n cases, d dimensions) that will be used. One DataPoint per row or symmetric Distance matrix [1:n,1:n] |
| BestMatches | [1:n,1:2] Matrix with positions of Bestmatches=ProjectedPoints, one matrix line per data point |
| LC | grid size c(Lines,Columns) |
| StructureType | Optional, bool; =TRUE: compact structure of clusters assumed, =FALSE: connected structure of clusters assumed. For the two options vor Clusters, see [Thrun, 2018] or Handl et al. 2006 |
| PlotIt | Optional, bool, Plots Dendrogramm |
| method | Optional, one of 39 distance methods of parDist of package parallelDist, if Data matrix is chosen above |
| ... | Further arguments passed on to the parDist function, e.g. user-defined distance functions |

Details

DBS is a flexible and robust clustering framework that consists of three independent modules. The first module is the parameter-free projection method Pswarm [Pswarm](#), which exploits the concepts of self-organization and emergence, game theory, swarm intelligence and symmetry considerations. The second module is a parameter-free high-dimensional data visualization technique, which generates projected points on a topographic map with hypsometric colors [GeneratePswarmVisualization](#), called the generalized U-matrix. The third module is a clustering method with no sensitive parameters [DBSclustering](#) (see [Thrun, 2018, p. 104 ff]). The clustering can be verified by the visualization and vice versa. The term DBS refers to the method as a whole.

Value

Cls [1:n] vector with selected classes of the bestmatches. You can use `plotTopographicMap(Umatrix,Bestmatches,Cls)` for verification.

Note

If you used `pswarm` with distance matrix instead of a data matrix you may transform your distances into data by using MDS of the `ProjectionBasedClustering` package. The correct dimension can be found through the Shepard diagram or kruskals stress.

Often it is better to mark the outliers manually after the prozess of clustering and sometimes a clustering can be improved through human interaction [Thrun/Ultsch,2017] <DOI:10.13140/RG.2.2.13124.53124>; use in this case the visualization `plotTopographicMap` of the package `GeneralizedUmatrix`. If you would like to mark the outliers interactivly in the visualization use the `Umatrix` package in <https://www.uni-marburg.de/fb12/datenbionik/software-en> or the function `interactiveClustering()` of the `ProjectionBasedClustering` package on CRAN.

If you want to verify your clustering result externally, you can use `Heatmap` or `SilhouettePlot` of the CRAN package `DataVisualizations`.

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

Examples

```
data("Lsun3D")
Data=Lsun3D$Data
InputDistances=as.matrix(dist(Data))

projection=Pswarm(InputDistances)
#automatic Clustering without GeneralizedUmatrix visualization
Cls=DBSclustering(k=3, Data,

projection$ProjectedPoints, projection$LC,PlotIt=TRUE)

## Not run:
visualization=GeneratePswarmVisualization(Data,

projection$ProjectedPoints,projection$LC)
## Sometimes an automatic Clustering can be improved
## thorough an interactive approach,
## e.g. if Outliers exist (see [Thrun/Ultsch, 2017])
library(ProjectionBasedClustering)
Cls2=ProjectionBasedClustering::interactiveClustering(visualization$Umatrix,
visualization$Bestmatches, Cls)
```

```
## End(Not run)
```

DefaultColorSequence *Default color sequence for plots*

Description

Defines the default color sequence for plots made within the Projections package.

Usage

```
data("DefaultColorSequence")
```

Format

A vector with 562 different strings describing colors for plots.

Delaunay4Points *Adjacency matrix of the delaunay graph for BestMatches of Points*

Description

Calculates the adjacency matrix of the delaunay graph for BestMatches (BM's) in tiled form if BestMatches are located on a toroid grid

Usage

```
Delaunay4Points(Points, IsToroid = TRUE, Grid=NULL, PlotIt=FALSE, Gabriel=FALSE)
```

Arguments

| | |
|----------|--|
| Points | [1:n,1:3] matrix containing the BMKey, X and Y coordinates of the n, BestMatches NEED NOT to be UNIQUE, however, there is an edge in the Deaunay between duplicate points! |
| IsToroid | Optional, logical, indicating if BM's are on a toroid grid. Default is True |
| Grid | Optional, A vector of length 2, containing the number of lines and columns of the Grid |
| PlotIt | Optional, bool, Plots the graph |
| Gabriel | Optional, bool, default: FALSE, If TRUE: calculates the gabriel graph instead of the delaunay graph |

Value

Delaunay[1:n,1:n] adjacency matrix of the Delaunay-Graph

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

DelaunayClassificationError

Delaunay Classification Error (DCE)

Description

DCE searches for the k-nearest neighbors of the first delaunay neighbors weighted by the Euclidean Distances of the Inputspace. DCE evaluates these neighbors in the Output space. A low value indicates a better two-dimensional projection of the high-dimensional Input space.

Usage

```
DelaunayClassificationError(Data,ProjectedPoints,Cls,LC=NULL)
```

Arguments

| | |
|-----------------|---|
| Data | [1:n,1:d] |
| ProjectedPoints | [1:n,1:2] |
| Cls | [1:n,1] |
| LC | Optional, default NULL, Wenn toroid, muss c(Lines,Columns) angegeben werden |

Details

Delaunay classification error (DCE) makes an unbiased evaluation of distance and densitybased structure which ma be even non-linear seperable. First, DCE utilizes the information provided by a prior classification to assess projected structures. Second, DCE applies the insights drawn from graph theory. Details are described in [Thrun/Ultsch, 2018]

Value

list of

DCE DelaunayClassificationError NOTE the rest is just for development purposes

DCEperPoint(1:n) unnormalized DCE of each point: $DCE = \text{mean}(DCEperPoint)$

nn the number of points in a relevant neighborhood: $0.5 * 85\text{percentile}(AnzNN)$

AnzNN(1:n) the number of points with a delaunay graph neighborhood

NNdists(1:n,1:nn) the distances within the relevant neighborhood, 0 for inner cluster distances

HD(1:nn) HD = HarmonicDecay(nn) i.e weight function for the NNdists: $DCEperPoint = HD * NNdists$

Note

see also chapter 6 of [Thrun, 2018]

Author(s)

Michael Thrun

References

[Thrun/Ultsch, 2018] Thrun, M. C., & Ultsch, A. : Investigating Quality measurements of projections for the Evaluation of Distance and Density-based Structures of High-Dimensional Data, Proc. European Conference on Data Analysis (ECDA), pp. accepted, Paderborn, Germany, 2018.

Examples

```
data(Hepta)
```

```
InputDistances=as.matrix(dist(Hepta$Data))
```

```
projection=Pswarm(InputDistances)
```

```
DelaunayClassificationError(Hepta$Data,projection$ProjectedPoints,Hepta$Cls,LC=projection$LC)$DCE
```

Delta3DWeightsC

Intern function

Description

Implementation of the main equation for SOM, ESOM or the sESOM algorithms

Usage

```
Delta3DWeightsC(vx,Datasample)
```

Arguments

`vx` array of weights [1:Lines,1:Columns,1:Weights]
`Datasample` NumericVector of one Datapoint[1:n]

Details

intern function in case of `ComputeInR==FALSE` in [GeneratePswarmVisualization](#), see chapter 5.3 of [Thrun, 2018] for generalized Umatrix and especially the sESOM4BMUs algorithm.

Value

modified array of weights [1:Lines,1:Columns,1:]

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

DijkstraSSSP

Internal function: Dijkstra SSSP

Description

Dijkstra's SSSP (Single source shortest path) algorithm:

gets the shortest path (geodesic distance) from source vertice(point) to all other vertices(points) defined by the edges of the adjasency matrix

Usage

`DijkstraSSSP(Adj, Costs, source)`

Arguments

`Adj` [1:n,1:n] 0/1 adjascency matrix, e.g. from delaunay graph or gabriel graph
`Costs` [1:n,1:n] matrix, distances between n points (normally euclidean)
`source` int, vertice(point) from which to calculate the geodesic distance to all other points

Details

Preallocating space for DataStructures accordingly to the maximum possible number of vertices which is fixed set at the number 10001. This is an internal function of `ShortestGraphPathsC`, no errors or mis-usage is caught here.

Value

ShortestPaths[1:n] vector, shortest paths (geodesic) to all other vertices including the source vertice itself

Note

runs in $O(E \cdot \log(V))$

Author(s)

Michael Thrun

References

uses a changed code which is inspired by Shreyans Sheth 28.05.2015, see <http://ideone.com/qkmt31>

findPossiblePositionsCsingle

Intern function, do not use yourself

Description

Finds all possible jumping position regarding a grid and a Radius for DataBots

Usage

```
findPossiblePositionsCsingle(RadiusPositionsschablone,
    jumplength, alpha, Lines)
```

Arguments

| | |
|--------------------------|--|
| RadiusPositionsschablone | NumericMatrix, see setPolarGrid |
| jumplength | double radius of databots regarding neighborhood, they can jump to |
| alpha | double, zu streichen |
| Lines | double, jumplength has to smaller than Lines/2 and Lines/2 has to yield to a integer number. |

Details

Algorithm is described in [Thrun, 2018, p. 95, Listing 8.1].

Value

OpenPositions NumericMatrix, indices of open positions

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

See Also

[setPolarGrid](#)

GeneratePswarmVisualization

Generates the Umatrix for Pswarm algorithm

Description

Generates the special case of the generalized Umatrix with the help of an unsupervised neural network (here self-organizing map). From the generalized Umatrix a topographic map with hypsometric tints can be derived. To see this visualization use `plotTopographicMap` of the package `GeneralizedUmatrix`.

Usage

```
GeneratePswarmVisualization(Data,ProjectedPoints,LC,PlotIt=FALSE,ComputeInR=FALSE)
```

Arguments

Data [1:n,1:d] array of data: n cases in rows, d variables in columns

ProjectedPoints

matrix, ProjectedPoints[1:n,1:2] n by 2 matrix containing coordinates of the Projection: A matrix of the fitted configuration. see output of `Pswarm` for further details

| | |
|------------|---|
| LC | size of the grid <code>c(Lines,Columns)</code> , number of Lines and Columns automatic calculated by <code>setGridSize</code> in <code>Pswarm</code> Sometimes is better to choose a different grid size, e.g. to reduce computational effort contrary to SOM, here the grid size defined only the resolution of the visualizations The real grid size is predefined by <code>Pswarm</code> , but you may choose a factor <code>x*res\$LC</code> if you so desire. Therefore, The resulting grid size is given back in the Output. |
| PlotIt | Optional, default(<code>FALSE</code>), If <code>TRUE</code> than uses <code>plotTopographicMap</code> of the package <code>GeneralizedUmatrix</code> |
| ComputeInR | Optional, <code>=TRUE</code> : Rcode, <code>=FALSE</code> C++ implementation |

Details

DBS is a flexible and robust clustering framework that consists of three independent modules. The first module is the parameter-free projection method `Pswarm` `Pswarm`, which exploits the concepts of self-organization and emergence, game theory, swarm intelligence and symmetry considerations. The second module is a parameter-free high-dimensional data visualization technique, which generates projected points on a topographic map with hypsometric colors `GeneratePswarmVisualization`, called the generalized U-matrix. The third module is a clustering method with no sensitive parameters `DBSclustering`. The clustering can be verified by the visualization and vice versa. The term DBS refers to the method as a whole.

see chapter 8 of [Thrun, 2018] for `Pswarm`

chapter 5.3 of [Thrun, 2018] for generalized Umatrix and especially the `sESOM4BMUs` algorithm.

Value

list of

| | |
|------------------|--|
| Bestmatches | matrix [1:n,1:2], BestMatches of the Umatrix, contrary to ESOM they are always fixed, because predefined by <code>GridPoints</code> . |
| Umatrix | matrix [1:Lines,1:Columns], |
| WeightsOfNeurons | array [1:Lines,1:Columns,1:d], d is the dimension of the weights, the same as in the ESOM algorithm |
| GridPoints | matrix [1:n,1:2],quantized projected points: projected points now lie on a predefined grid. |
| LC | <code>c(Lines,Columns)</code> , normally equal to grid size of <code>Pswarm</code> , sometimes it a better or a lower resolution for the visualization is better. Therefore here the grid size of the neurons is given back. |

Note

If you used `pswarm` with distance matrix instead of a data matrix you can `mds` transform your distances into data (see the `MDS` function of the `ProjectionBasedClustering` package.). The correct dimension can be found through the Sheppard diagram or `kruskals` stress.

Note

For interactive Island Generation of an generalized Umatrix see `interactiveGeneralizedUmatrixIsland` function in the package `GeneralizedUmatrix`.

The main code of both functions `GeneralizedUmatrix` and `GeneratePswarmVisualization` is the same C++ function `sESOM4BMUs` which is described in [Thrun, 2018].

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

See Also

`Pswarm` and `plotTopographicMap` and `GeneralizedUmatrix` of the package `GeneralizedUmatrix`

Examples

```
data("Lsun3D")
Data=Lsun3D$Data
Cls=Lsun3D$Cls
InputDistances=as.matrix(dist(Data))

res=Pswarm(InputDistances)
resUmatrix=GeneratePswarmVisualization(Data,res$ProjectedPoints,res$LC)
library(GeneralizedUmatrix)
plotTopographicMap(resUmatrix$Umatrix,resUmatrix$Bestmatches,Cls)
```

getCartesianCoordinates

Intern function: Transformation of Databot indizes to coordinates

Description

Transforms Databot indizes to exact cartesian coordinates on an toroid two dimensional grid.

Arguments

| | |
|---------------------------|--|
| DataBotsPos[1:N] | complex vector Two Indizes per Databot describing its positions in an two dimensional grid |
| GridRadius[Lines,Columns] | Radii Matrix of all possible Positions of DataBots in Grid, see also documentation of setPolarGrid |
| GridAngle[Lines,Columns] | Angle Matrix of all possible Positions of DataBots in Grid, see also documentation of setPolarGrid |
| Lines,Columns | Size of planar toroid two dimensional grid |
| QuadOrHexa | Optional, FALSE=If DataPos on hexadiagonal grid, round to 2 decimals after value, Default=TRUE |

Details

Transformation is described in [Thrun, 2018, p. 93].

Value

BestMatchingUnits[1:N,2] coordinates on an two dimensional grid for each databot excluding unique key, such that by using [GeneratePswarmVisualization](#) a visualization of the Pswarm projection is possible

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

getUmatrix4Projection *depricated! see GeneralizedUmatrix() Generalisierte U-Matrix fuer Projektionsverfahren*

Description

depricated! see GeneralizedUmatrix()

Usage

```
getUmatrix4Projection(Data,ProjectedPoints,
PlotIt=TRUE,Cls=NULL,toroid=T,Tiled=F,ComputeInR=F)
```

Arguments

| | |
|-----------------|--|
| Data | [1:n,1:d] array of data: n cases in rows, d variables in columns |
| ProjectedPoints | [1:n,2]n by 2 matrix containing coordinates of the Projection: A matrix of the fitted configuration. |
| PlotIt | Optional,bool, default=FALSE, if =TRUE: U-Marix of every current Position of Databots will be shown |
| Cls | Optional, For plotting, see plotUmatrix in package Umatrix |
| toroid | Optional, Default=FALSE, ==FALSE planar computation ==TRUE: toroid borderless computation, set so only if projection method is also toroidal |
| Tiled | Optional,For plotting see plotUmatrix in package Umatrix |
| ComputeInR | Optional, =T: Rcode, =F Cpp Code |

Value

| | |
|----------------------|--|
| List with | |
| Umatrix | [1:Lines,1:Columns] (see ReadUMX in package DataIO) |
| EsomNeurons | [Lines,Columns,weights] 3-dimensional numeric array (wide format), not wts (long format) |
| Bestmatches | [1:n,OutputDimension] GridConverted Projected Points information converted by convertProjectionProjectedPoints() to predefined Grid by Lines and Columns |
| gplotres | Ausgabe von ggplot |
| unbesetztePositionen | Umatrix[unbesetztePositionen] =NA |

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, ISBN: 978-3-658-20539-3, Heidelberg, 2018.

Examples

```

data("Lsun3D")
Data=Lsun3D$Data
Cls=Lsun3D$Cls
InputDistances=as.matrix(dist(Data))
res=cmdscale(d=InputDistances, k = 2, eig = TRUE, add = FALSE, x.ret = FALSE)
ProjectedPoints=as.matrix(res$points)
# Stress = KruskalStress(InputDistances, as.matrix(dist(ProjectedPoints)))
#resUmatrix=GeneralizedUmatrix(Data,ProjectedPoints)
#plotTopographicMap(resUmatrix$Umatrix,resUmatrix$Bestmatches,Cls)

```

Hepta

Hepta form FCPS

Description

clearly defined clusters, different variances

Usage

```
data("Hepta")
```

Details

Size 212, Dimensions 3, stored in Hepta\$Data

Classes 7, stored in Hepta\$C1s

References

Ultsch, A.: Clustering with SOM: U*C, In Proc. Workshop on Self-Organizing Maps, Paris, France, (2005) , pp. 75-82

Examples

```
data(Hepta)  
str(Hepta)
```

Lsun3D

Lsun3D inspired by FCPS

Description

clearly defined clusters, different variances

Usage

```
data("Lsun3D")
```

Details

Size 404, Dimensions 3

Dataset defined discontinuities, where the clusters have different variances. Three main Clusters, and four Outliers (in Cluster 4). See for a more detailed description in [Thrun, 2018].

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

Examples

```
data(Lsun3D)
str(Lsun3D)
Cls=Lsun3D$Cls
Data=Lsun3D$Data
```

plotSwarm

Intern function for plotting during the Pswarm annealing process

Description

Intern function, generates a scatter plot of the progress of the Pswarm algorithm after every nash equilibrium. Every point symbolizes a Databot. If a prior classification is given (Cls) then the Databots have the colors defined by the class labels.

Usage

```
plotSwarm(Points,Cls,xlab,ylab,main)
```

Arguments

| | |
|--------|---|
| Points | ProjectedPoints or DataBot positions in cartesian coordinates |
| Cls | optional, Classification as a numeric vector, if given |
| xlab | = 'X', optional, string |
| ylab | = 'Y', optional, string |
| main | = "DataBots", optional, string |

Author(s)

Michael Thrun

See Also

[Pswarm](#) with PlotIt=TRUE

ProjectedPoints2Grid *Transforms ProjectedPoints to a grid*

Description

quantized xy cartesian coordinates of ProjectedPoints

Usage

```
ProjectedPoints2Grid(ProjectedPoints, Lines, Columns, PlotIt)
```

Arguments

| | |
|-----------------|--|
| ProjectedPoints | [1:n,1:2] matrix of cartesian xy coordinates |
| Lines | double, length of small side of the rectangular grid |
| Columns | double, length of big side of the rectangular grid |
| PlotIt | optional, bool, shows the result if TRUE |

Details

intern function, described in [Thrun, 2018, p.47]

Value

BestMatches[1:n,1:3] columns in order: Key,Lines,Columns

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

See Also

[GeneratePswarmVisualization](#)

Pswarm

*A Swarm of Databots based on polar coordinates (Polar Swarm).***Description**

This projection method is a part of the databionic swarm which uses the nash equilibrium. Using polar coordinates for agents (here Databots) in two dimensions has many advantages, for further details see [Thrun, 2018].

Usage

```
Pswarm(DataOrDistance,PlotIt=F,Cls=NULL,Silent=T,
       Debug=FALSE,LC=c(NULL,NULL),method= "euclidean",...)
```

Arguments

| | |
|----------------|--|
| DataOrDistance | matrix, DataOrDistance[1:n,1:n] symmetric matrix of dissimilarities, if variable unsymmetric DataOrDistance[1:d,1:n] is assumed as a dataset and the euclidean distances are calculated of d variables and n cases |
| PlotIt | Optional, bool, default=FALSE, If =TRUE, Plots the projection during the computation prozess after every nash equilbirum |
| Cls | Optional, numeric vector [1:n], given Classification in numbers, only for plotting if PlotIt=TRUE, irrelevant for computations |
| Silent | Optional, bool, default=FALSE, If =TRUE results in various console messages |
| Debug | Optional, Debug, default=FALSE, =TRUE results in various console messages, deprecated for CRAN, because cout is not allowed. |
| LC | Optional, grid size c(Lines, Columns), sometimes it is better to call setGridSize separately. |
| method | Optional, one of 39 distance methods of parDist of package parallelDist, if Data matrix is chosen above |
| ... | Further arguments passed on to the parDist function, e.g. user-defined distance functions |

Details

DBS is a flexible and robust clustering framework that consists of three independent modules. The first module is the parameter-free projection method Pswarm [Pswarm](#), which exploits the concepts of self-organization and emergence, game theory, swarm intelligence and symmetry considerations. The second module is a parameter-free high-dimensional data visualization technique, which generates projected points on a topographic map with hypsometric colors [GeneratePswarmVisualization](#), called the generalized U-matrix. The third module is a clustering method with no sensitive parameters [DBSclustering](#). The clustering can be verified by the visualization and vice versa. The term DBS refers to the method as a whole.

Value

| | |
|-----------------|--|
| List with | |
| ProjectedPoints | [1:n,1:2] xy cartesian coordinates of projection |
| LC | number of Lines and Columns in c(Lines,Columns) |
| Control | List, only for intern debugging |

Note

LC is now automatically estimated; LC is the size of the grid c(Lines,Columns), number of Lines and Columns, default c(NULL,NULL) and automatic calculation by [setGridSize](#)

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

Examples

```
data("Lsun3D")
Data=Lsun3D$Data
Cls=Lsun3D$Cls
InputDistances=as.matrix(dist(Data))
#If not called separately setGridSize() is called in Pswarm
LC=setGridSize(InputDistances)
res=Pswarm(InputDistances,LC=LC,Cls=Cls,PlotIt=TRUE)
```

PswarmCurrentRadiusC2botsPositive

intern function, do not use yourself

Description

Finds the weak Nash equilibrium for DataBots in one epoch(Radius), requires the setting of constants, grid, and so on in [Pswarm](#)

Usage

```
PswarmCurrentRadiusC2botsPositive( AllDataBotsPosOld,
  Radius, DataDists,
  IndPossibleDBPosR,
  RadiusPositionsschablone, pp,
  Nullpunkt, Lines, Columns,
  nBots, limit, steigungsverlaufind, StressConstAditiv, debug)
```

Arguments

| | |
|--------------------------|---|
| AllDataBotsPosOld | ComplexVector [1:n,1], DataBots position in the last Nash-Equilibrium |
| Radius | double, Radius of payoff function, neighborhood, where other DatsBots can be smelled |
| DataDists | NumericMatrix, Inputdistances[1:n,1:n] |
| IndPossibleDBPosR | ComplexVector, see output of findPossiblePositionsCsingle |
| RadiusPositionsschablone | NumericMatrix, see AllallowedDBPosR0 in setPolarGrid |
| pp | NumericVector, number of jumping simultaneously DataBots of one eepoch (per nash-equilibirum), this vector is linearly monotonically decreasing |
| Nullpunkt | NumericVector, equals which(AllallowedDBPosR0==0, arr.ind=T), see see AllallowedDBPosR0 in setPolarGrid |
| Lines | double, small edge length of rectangulare grid |
| Columns | double, big edge length of rectangulare grid |
| nBots | double, intern constant, equals round(pp[Radius]*DBAnzahl) |
| limit | int, intern constant, equals ceiling(1/pp[Radius]) |
| steigungsverlaufind | int, intern constant |
| StressConstAditiv | double, intern constant, sum of payoff of all databots in random condition before the algorithm starts |
| debug | optional, bool: If TRUE prints status every 100 iterations |

Details

Algorithm is described in [Thrun, 2018, p. 95, Listing 8.1].

Value

| | |
|-------------------|--|
| list of | |
| AllDataBotsPos | ComplexVector, indizes of DataBot Positions after a weak Nash equilibrium is found |
| stressverlauf | NumericVector, intern result, for debugging only |
| fokussiertlaufind | NumericVector, intern result, for debugging only |

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

 rDistanceToroidCsingle

Intern function for Pswarm

Description

toroid distance calculation

Usage

```
rDistanceToroidCsingle( AllDataBotsPosX,
  AllDataBotsPosY, AllallowedDBPosR0,
  Lines, Columns, Nullpunkt)
```

Arguments

| | |
|-------------------|---|
| AllDataBotsPosX | NumericVector [1:n,1], positions of on grid |
| AllDataBotsPosY | NumericVector [1:n,1], positions of on grid |
| AllallowedDBPosR0 | NumericMatrix |
| Lines | double |
| Columns | double |
| Nullpunkt | NumericVector |

Details

Part of the algorithm described in [Thrun, 2018, p. 95, Listing 8.1].

Value

numeric matrix of toroid Distances[1:n,1:n]

Note

do not use yourself

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

See Also[Pswarm](#)

| | |
|--------------------|----------------------------|
| RelativeDifference | <i>Relative Difference</i> |
|--------------------|----------------------------|

Description

Calculates the difference between positive x and y values

Usage

```
RelativeDifference(X, Y, epsilon = 10^-10)
```

Arguments

| | |
|---------|---|
| X | either a value or numerical vector of [1:n] |
| Y | either a value or numerical vector of [1:n] |
| epsilon | If both x and y are approximatly zero the output is also zero |

Details

Contrary to other approaches in this cases the range of values lies between [-2,2]. The approach is only valid for positive values of X and Y. The realtive difference R is defined with

$$R = \frac{Y - X}{0.5 * (X + Y)}$$

Negative value indicate that X is higher than Y and positive values that X is lower than Y.

Value

R

Note

It can be combined with the DelaunayClassificationError if a clear baseline is defined.

Author(s)

Michael Thrun

References

Ultsch, A.: Is Log Ratio a Good Value for Measuring Return in Stock Investments? GfKl 2008, pp, 505-511, 2008.

See Also

[DelaunayClassificationError](#)

Examples

```
x=c(1:5)
y=runif(5,min=1,max=10)
RelativeDifference(x,y)
```

RobustNormalization *RobustNormalization*

Description

RobustNormalization as described in [Milligan/Cooper, 1988].

Usage

```
RobustNormalization(Data,Centered=FALSE,Capped=FALSE,na.rm=TRUE)
```

Arguments

| | |
|----------|---|
| Data | [1:n,1:d] |
| Centered | centered data around zero by median if TRUE |
| Capped | TRUE: Outliers are capped above 1 or below -1 and set to 1 or -1. |
| na.rm | If TRUE, infinite vlaues are disregarded |

Details

Range of most of values for each feature is not between zero and one. Fpr a more precise description please read [Thrun, 2018, p.17].

Value

TransformedData[1:n,1:d]

Author(s)

Michael Thrun

References

[Milligan/Cooper, 1988] Milligan, G. W., & Cooper, M. C.: A study of standardization of variables in cluster analysis, *Journal of Classification*, Vol. 5(2), pp. 181-204. 1988.

[Thrun, 2018] Thrun, M. C.: *Projection Based Clustering through Self-Organization and Swarm Intelligence*, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

sESOM4BMUs

Intern function: Simplified Emergent Self-Organizing Map

Description

Intern function for the simplified ESOM (sESOM) algorithm for fixed BestMatchingUnits

Usage

sESOM4BMUs(BMUs,Data, esom, toroid, CurrentRadius,ComputeInR)

Arguments

| | |
|---------------|---|
| BMUs | [1:Lines,1:Columns], BestMAatchingUnits generated by ProjectedPoints2Grid() |
| Data | [1:n,1:d] array of data: n cases in rows, d variables in columns |
| esom | [1:Lines,1:Columns,1:weights] array of NeuronWeights, see ListAsEsomNeurons() |
| toroid | TRUE/FALSE - topology of points |
| CurrentRadius | number between 1 to x |
| ComputeInR | =T: Rcode, =F Cpp Codenumber between 1 to x |

Details

Algorithm is described in [Thrun, 2018, p. 48, Listing 5.1].

Value

| | |
|------|--|
| esom | array [1:Lines,1:Columns,1:d], d is the dimension of the weights, the same as in the ESOM algorithm. modified esomneuros regarding a predefined neighborhood defined by a radius |
|------|--|

Note

Usually not for seperated usage!

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

See Also

[GeneratePswarmVisualization](#)

| | |
|---------------|--|
| setdiffMatrix | <i>setdiffMatrix shortens Matrix2Curt by those rows that are in both matrices.</i> |
|---------------|--|

Description

setdiffMatrix shortens Matrix2Curt by those rows that are in both matrices.

Arguments

Matrix2Curt[n,k]

matrix, which will be shortened by x rows

Matrix2compare[m,k]

matrix whose rows will be compared to those of Matrix2Curt x rows in Matrix2compare equal rows of Matrix2Curt (order of rows is irrelevant). Has the same number of columns as Matrix2Curt.

Value

V\$CurtedMatrix[n-x,k] Shortened Matrix2Curt

Author(s)

CL,MT 12/2014

| | |
|-------------|--|
| setGridSize | <i>Sets the grid size for the Pswarm algorithm</i> |
|-------------|--|

Description

Automatically sets the size of the grid, formula see [Thrun, 2018, p. 93-94].

Usage

```
setGridSize(InputDistances,minp=0.01,maxp=0.99,alpha=4)
```

Arguments

| | |
|----------------|--|
| InputDistances | [1:n,1:n] symmetric matrix of input distances |
| minp | default value: 0.01, see quantile , first value in the vector of probs estimates robust minimum of distances |
| maxp | default value: 0.99, see quantile , last value of the vector of probs estimates robust maximum of distances |
| alpha | Do not change! Intern parameter, Only if Java Version of Pswarm instead of C++ version is used. |

Details

grid is set such that minimum and maximum distances can be shown on the grid

Value

LC=c(Lines,Columns) size of the grid for Pswarm

Author(s)

Michael Thrun, Florian Lerch

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

See Also

automatic choice of LC for [Pswarm](#)

Examples

```
data("Lsun3D")
Data=Lsun3D$Data
Cls=Lsun3D$Cls
InputDistances=as.matrix(dist(Data))
#If not called separately setGridSize() is called in Pswarm
LC=setGridSize(InputDistances)
```

setPolarGrid *Intern function: Sets the polar grid*

Description

Sets a polar grid for a swarm in an rectangular shape

Usage

```
setPolarGrid(Lines,Columns,QuadOrHexa,PlotIt,global)
```

Arguments

| | |
|------------|---|
| Lines | Integer, hast to be able to be divided by 2 |
| Columns | Integer, with Columns>=Lines |
| QuadOrHexa | bool, default(TRUE) If False Hexagonal grid, default quad grid |
| PlotIt | bool, default(FALSE) |
| global | bool, default(TRUE), intern parameter, how shall the radii be calculated? |

Details

Part of the Algorithm described in [Thrun, 2018, p. 95, Listing 8.1].

Value

| | |
|---------------------|--|
| list of | |
| GridRadii | matrix [1:Lines,1:Columns], Radii Matrix of all possible Positions of DataBots in Grid |
| GridAngle | matrix [1:Lines,1:Columns], Angle Matrix of all possible Positions of DataBots in Grid |
| AllallowedDBPosR0 | matrix [1:Lines+1,1:Columns+1], Matrix of radii in polar coordinates respecting origin (0,0) of all allowed DataBots Positions in one jump |
| AllallowedDBPosPhi0 | matrix [1:Lines+1,1:Columns+1], # V\$AllallowedDBPosPhi0[Lines+1,Lines+1] Matrix of angle in polar coordinates respecting origin (0,0) of all allowed DataBots Positions in one jump |

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

See Also[Pswarm](#)

`setRmin`*Intern function: Estimates the minimal radius for the Databot scent*

Description

estimates the minimal radius on apolar grid in the automated annealing process of Pswarm, details of how can be read in [Thrun, 2018, p. 97]

Arguments

| | |
|-------------------|---|
| Lines | x-value determining the size of the map, i.e. how many open places for DataBots will be available on the 2-dimensional grid BEWARE: has to be able to be divided by 2 |
| Columns | y-value determining the size of the map, i.e. how many open places for DataBots will be available on the 2-dimensional grid Columns>Lines |
| AllallowedDBPosR0 | [1:Lines+1,1:Lines+1]Matrix of radii in polar coordinates respecting origin (0,0) of all allowed DataBots Positions in one jump |
| p | percent of gitterpositions, which should be considered |

Value

Rmin Minimum Radius

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

ShortestGraphPathsC *Shortest GraphPaths = geodesic distances*

Description

Dijkstra's SSSP (Single source shortest path) algorithm, from all points to all points

Usage

ShortestGraphPathsC(Adj, Cost)

Arguments

Adj [1:n,1:n] 0/1 adjascency matrix, e.g. from delaunay graph or gabriel graph
Cost [1:n,1:n] matrix, distances between n points (normally euclidean)

Details

Vertices are the points, edges have the costs defined by weights (normally a distance). The algorithm runs in runs in $O(n \cdot E \cdot \log(V))$, see also [Jungnickel, 2013, p. 87]. Further details can be found in [Jungnickel, 2013, p. 83-87] and [Thrun, 2018, p. 12].

Value

ShortestPaths[1:n,1:n] vector, shortest paths (geodesic) to all other vertices including the source vertice itself from al vertices to all vertices, stored as a matrix

Note

require C++11 standard (set flag in Compiler, if not set automatically)

Author(s)

Michael Thrun

References

- [Dijkstra,1959] Dijkstra, E. W.: A note on two problems in connexion with graphs, Numerische mathematik, Vol. 1(1), pp. 269-271. 1959.
- [Jungnickel, 2013] Jungnickel, D.: Graphs, networks and algorithms, (4th ed ed. Vol. 5), Berlin, Heidelberg, Germany, Springer, ISBN: 978-3-642-32278-5, 2013.
- [Thrun/Ultsch, 2017] Thrun, M.C., Ultsch, A.: Projection based Clustering, Conf. Int. Federation of Classification Societies (IFCS),DOI:10.13140/RG.2.2.13124.53124, Tokyo, 2017.
- [Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

See Also[DijkstraSSSP](#)

`trainstepC`*Internal function for sESOM*

Description

Does the training for fixed bestmatches in one epoch of the sESOM algorithm (see [Thrun, 2018] for details).

Usage

```
trainstepC(vx,vy, DataSampled,BMUsampled,Lines,Columns, Radius, toroid)
```

Arguments

| | |
|--------------------------|---|
| <code>vx</code> | array (1:Lines,1:Columns,1:Weights), WeightVectors that will be trained, internally transformed von NumericVector to cube |
| <code>vy</code> | array (1:Lines,1:Columns,1:2), meshgrid for output distance computation |
| <code>DataSampled</code> | NumericMatrix, n cases shuffled Dataset[1:n,1:d] by sample |
| <code>BMUsampled</code> | NumericMatrix, n cases shuffled BestMatches[1:n,1:2] by sample in the same way as DataSampled |
| <code>Lines</code> | double, Height of the grid |
| <code>Columns</code> | double, Width of the grid |
| <code>Radius</code> | double, The current Radius that should be used to define neighbours to the bm |
| <code>toroid</code> | bool, Should the grid be considered with cyclically connected borders? |

Details

Algorithm is described in [Thrun, 2018, p. 48, Listing 5.1].

Value

WeightVectors, array[1:Lines,1:Columns,1:weights] with the adjusted Weights

Note

Usually not for seperated usage!

Author(s)

Michael Thrun

References

[Thrun, 2018] Thrun, M. C.: Projection Based Clustering through Self-Organization and Swarm Intelligence, doctoral dissertation 2017, Springer, Heidelberg, ISBN: 978-3-658-20539-3, <https://doi.org/10.1007/978-3-658-20540-9>, 2018.

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