

Table of Contents

Introduction	1
Part I. Genetic Algorithms	11
1 GAs: What Are They?	13
1.1 Optimization of a simple function	18
1.1.1 Representation	19
1.1.2 Initial population	20
1.1.3 Evaluation function	20
1.1.4 Genetic operators	21
1.1.5 Parameters	21
1.1.6 Experimental results	22
1.2 The prisoner's dilemma	22
1.2.1 Representing a strategy	23
1.2.2 Outline of the genetic algorithm	23
1.2.3 Experimental results	24
1.3 Traveling salesman problem	25
1.4 Hill climbing, simulated annealing, and genetic algorithms	26
1.5 Conclusions	30
2 GAs: How Do They Work?	33
3 GAs: Why Do They Work?	45
4 GAs: Selected Topics	57
4.1 Sampling mechanism	58
4.2 Characteristics of the function	65
4.3 Contractive mapping genetic algorithms	68
4.4 Genetic algorithms with varying population size	72
4.5 Genetic algorithms, constraints, and the knapsack problem	80
4.5.1 The 0/1 knapsack problem and the test data	81
4.5.2 Description of the algorithms	82
4.5.3 Experiments and results	84
4.6 Other ideas	88

Part II. Numerical Optimization	95
5 Binary or Float?	97
5.1 The test case	100
5.2 The two implementations	100
5.2.1 The binary implementation	100
5.2.2 The floating point implementation	101
5.3 The experiments	101
5.3.1 Random mutation and crossover	101
5.3.2 Non-uniform mutation	103
5.3.3 Other operators	104
5.4 Time performance	105
5.5 Conclusions	105
6 Fine Local Tuning	107
6.1 The test cases	108
6.1.1 The linear-quadratic problem	109
6.1.2 The harvest problem	109
6.1.3 The push-cart problem	110
6.2 The evolution program for numerical optimization	110
6.2.1 The representation	111
6.2.2 The specialized operators	111
6.3 Experiments and results	113
6.4 Evolution program versus other methods	114
6.4.1 The linear-quadratic problem	114
6.4.2 The harvest problem	115
6.4.3 The push-cart problem	115
6.4.4 The significance of non-uniform mutation	117
6.5 Conclusions	118
7 Handling Constraints	121
7.1 An evolution program: the GENOCOP system	122
7.1.1 An example	125
7.1.2 Operators	127
7.1.3 Testing GENOCOP	130
7.2 Nonlinear optimization: GENOCOP II	134
7.3 Other techniques	141
7.3.1 Five test cases	144
7.3.2 Experiments	147
7.4 Other possibilities	150
7.5 GENOCOP III	154
8 Evolution Strategies and Other Methods	159
8.1 Evolution of evolution strategies	160
8.2 Comparison of evolution strategies and genetic algorithms	164
8.3 Multimodal and multiobjective function optimization	168

8.3.1	Multimodal optimization	168
8.3.2	Multiobjective optimization	171
8.4	Other evolution programs	172
Part III. Evolution Programs		179
9	The Transportation Problem	181
9.1	The linear transportation problem	181
9.1.1	Classical genetic algorithms	183
9.1.2	Incorporating problem-specific knowledge	185
9.1.3	A matrix as a representation structure	188
9.1.4	Conclusions	194
9.2	The nonlinear transportation problem	196
9.2.1	Representation	196
9.2.2	Initialization	196
9.2.3	Evaluation	196
9.2.4	Operators	196
9.2.5	Parameters	198
9.2.6	Test cases	198
9.2.6	Experiments and results	201
9.2.7	Conclusions	206
10	The Traveling Salesman Problem	209
11	Evolution Programs for Various Discrete Problems	239
11.1	Scheduling	239
11.2	The timetable problem	246
11.3	Partitioning objects and graphs	247
11.4	Path planning in a mobile robot environment	253
11.5	Remarks	261
12	Machine Learning	267
12.1	The Michigan approach	270
12.2	The Pitt approach	274
12.3	An evolution program: the GIL system	276
12.3.1	Data structures	276
12.3.2	Genetic operators	277
12.4	Comparison	280
12.5	REGAL	281
13	Evolutionary Programming and Genetic Programming	283
13.1	Evolutionary programming	283
13.2	Genetic programming	285
14	A Hierarchy of Evolution Programs	289

15 Evolution Programs and Heuristics	307
15.1 Techniques and heuristics: a summary	309
15.2 Feasible and infeasible solutions	312
15.3 Heuristics for evaluating individuals	314
Conclusions	329
Appendix A	337
Appendix B	349
Appendix C	353
Appendix D	359
References	363
Index	383