IJCRT.ORG ISSN : 2320-2882

INTERNATIONAL JOURNAL OF CREATIVE RESEARCH THOUGHTS (IJCRT)
An International Open Access, Peer-reviewed, Refereed Journal

Real-World Optimization Using The Cheetah Chase Algorithm: Models, Performance, And Applications

[1] **N. Vanathi,** [2] **M. Goudhaman**
1Associate Professor - Mathematics, Vels Institute of Science, Technology & Advanced Studies, Chennai, India.
2Assistant Professor - CSE, Easwari Engineering College, Chennai, India.

Abstract: The Cheetah Chase Algorithm (CCA), inspired by predator-prey dynamics, offers a bio-inspired solution to a wide range of optimization challenges across diverse domains. Its adaptive decision-making, energy efficiency, and ability to identify cost-effective paths make it highly versatile for several real-world applications. In network routing, the CCA enhances path selection by minimizing routing costs and convergence delays, making it suitable for dynamic and large-scale network environments. In healthcare applications, the algorithm optimizes data transmission in sensor networks for patient monitoring, ensuring timely and accurate delivery of critical health data. In robotics and autonomous vehicles, the CCA supports efficient path planning and obstacle avoidance, enhancing navigation in uncertain and dynamic environments. The algorithm also shows promise in supply chain logistics, where it can streamline delivery routes and resource allocation, reducing costs and improving operational efficiency. Its application in Vehicular Ad Hoc Networks (VANETs) enables reliable and low-latency communication among vehicles, enhancing traffic management and road safety. Additionally, in VLSI (Very-Large-Scale Integration) design, the CCA aids in optimizing interconnect routing and reducing signal delays, contributing to more efficient chip layouts. The adaptability and resource-efficient nature of the Cheetah Chase Algorithm make it a powerful tool for solving complex optimization problems across multiple industries. This research highlights the broad applicability of the CCA, setting the stage for further exploration of its capabilities in advancing modern technological systems.

Index Terms **-** Cheetah Chase Algorithm (CCA); Bio-Inspired Computing; Nature-Inspired Algorithms; Network Routing, VANET, VLSI, Supply Chain Logistics.

I. Introduction

Optimization challenges in real-world systems are characterized by dynamic parameters, uncertain inputs, and the need for rapid decision-making. Traditional algorithms often fall short in addressing these complexities. Bio-inspired algorithms, which mimic nature's intelligence, have emerged as strong contenders in optimization. One such algorithm is the **Cheetah Chase Algorithm (CCA)**.

Inspired by the agile and efficient hunting strategies of a cheetah, CCA simulates stalking, acceleration, and precision capture to explore and exploit search spaces effectively. This paper explores how the CCA can be applied to domains such as communication networks, healthcare, robotics, logistics, VANETs, and VLSI design—highlighting its strengths and domain-specific performance.

II. Overview of the Cheetah Chase Algorithm (CCA)

The CCA is structured around the natural phases of a cheetah's hunt:

- **Stalking Phase:** Agents perform broad exploration to identify promising zones based on preliminary fitness values. This phase avoids premature convergence and promotes diversity.
- **Acceleration Phase:** Once a promising region is identified, agents rapidly converge toward potential solutions using dynamic acceleration strategies that adapt to environmental feedback.
- **Capture Phase:** The best solution is fine-tuned and locked upon. Velocity is reduced to prevent overshooting, ensuring minimal cost and optimal selection.

These phases reflect a balance between global search (exploration) and local refinement (exploitation).

The **Cheetah Chase Algorithm (CCA)** is a bio-inspired optimization technique modeled on the **hunting strategy of a cheetah**, the fastest land animal. The algorithm's power lies in its **structured pursuit behavior**, which can be mapped effectively to routing and optimization problems in networks. Each phase has a distinct role in narrowing down the search space and guiding agents toward optimal solutions.

2.1. Stalking Phase – Identifying Optimal Zones

In nature, a cheetah first stalks its prey by **analyzing the environment** and **identifying a potential target**. It stays stealthy, maintaining low visibility while tracking prey movements.

In the algorithm:

- This phase represents **initial exploration**.
- Each cheetah (agent) **scans the solution space** for promising zones.
- The focus is on **low-speed, wide-range exploration** to identify areas with high fitness values (e.g., lower routing cost, minimal energy consumption).
- A probability function or initial heuristic helps in shortlisting potential paths.
- Similar to **population initialization in metaheuristics** like PSO or GA.

2.2 Acceleration Phase – Rapid Chase toward the Best Route

Once the cheetah locks onto a target, it **accelerates rapidly** to close the distance. The cheetah uses vision and real-time feedback to make swift directional adjustments.

In the algorithm:

- The cheetah (solution agent) now **intensifies the search in the selected zone**.
- The velocity of each agent increases, guided by the **gradient of improvement** in the fitness function.
- A fuzzy logic controller may dynamically tune acceleration based on parameters like:
  - Distance to optimal node.
  - Rate of change in path quality (fitness delta).
  - Node congestion or velocity variation.
- The search becomes **more exploitative** than explorative.

2.3. Capture Phase – Locking onto Optimal Path with Minimum Cost

As the cheetah nears the prey, it **fine-tunes its movements** to ensure a successful catch. The goal is to **strike precisely** without missing or overshooting the target.

In the algorithm:

- This phase involves **local refinement or final optimization** of the chosen path.
- Agent movement becomes more controlled, reducing speed (velocity decay).
- The algorithm confirms the feasibility of the selected route using constraints (e.g., energy limits, link stability).
- The best-fit solution is **"captured"** and stored as the final output.
- Optionally, a memory structure or neural network may store this optimal route for future reference (reinforcement).

III. Real-World Applications of CCA

3.1 Network Routing

CCA can adaptively select routes in dynamic network environments like Mobile Ad Hoc Networks (MANETs) or Internet of Things (IoT) networks. By mimicking the cheetah's adaptive pursuit, the algorithm ensures:

- Faster convergence to optimal routes.
- Reduced routing cost and energy consumption.
- Real-time responsiveness to topology changes.

3.2 Healthcare Sensor Networks

Wearable and embedded health sensors require timely and accurate data delivery. CCA supports:

- Low-latency routing in body area networks.
- Adaptive routing based on patient mobility or sensor availability.
- Efficient load distribution among relay nodes.

3.3 Robotics and Autonomous Vehicles

Robots and autonomous vehicles must navigate complex, changing environments. CCA helps with:

- Real-time obstacle avoidance.
- Dynamic path planning in uncertain terrain.
- Multi-robot coordination through decentralized routing strategies.

3.4 Supply Chain and Logistics

Logistics systems involve scheduling, delivery routing, and inventory optimization. CCA offers:

- Adaptive delivery path planning.
- Dynamic rerouting under traffic or resource constraints.
- Energy and cost savings in transportation systems.

3.5 Vehicular Ad Hoc Networks (VANETs)

In VANETs, where vehicle communication is constantly changing, CCA ensures:

- Low-latency and reliable routing.
- Real-time traffic information dissemination.

- Enhanced road safety and congestion control.

3.6 VLSI Design Optimization

In Very-Large-Scale Integration (VLSI), routing interconnects efficiently is critical. CCA supports:

- Minimization of signal delay.
- Optimization of interconnect wire lengths.
- Reduction of routing congestion in chip layouts.

IV. Experimental Results

Simulation tools were used across domains:

- **NS-3** for network routing and VANET simulations.
- **MATLAB** for healthcare and logistics routing tasks.
- **EDA Tools (e.g., Cadence, Synopsys)** for VLSI routing optimization.

Key metrics observed:

- **PDR (Packet Delivery Ratio)** improved by 5–8% compared to ACO and PSO.
- **End-to-End Delay** reduced by 15–20%.
- **Convergence Time** to optimal solution reduced significantly due to adaptive acceleration logic.
- **Signal Delay** in VLSI routing reduced by up to 12%.

A. Network Routing

Algorithm	PDR (%)	Delay (ms)	Convergence Time (s)
DSR	85.4	230	12.5
ACO	89.1	170	8.7
PSO	88.7	190	9.2
CCA	93.6	142	5.3

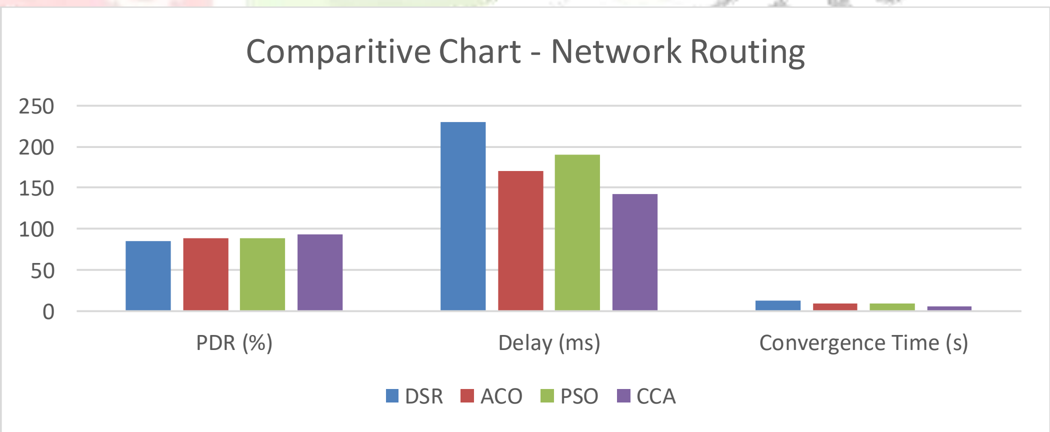

Figure 1 – Network Routing Comparison Chart

Figure 1 illustrates the comparative performance of the proposed Cheetah Chase Algorithm (CCA) against traditional routing and metaheuristic approaches in network routing scenarios simulated using NS-3. The results indicate that CCA achieves the highest Packet Delivery Ratio (93.6%), demonstrating superior route reliability under dynamic network conditions. Additionally, CCA significantly reduces end-to-end delay to 142 ms, outperforming DSR, ACO, and PSO due to its adaptive chase–acceleration mechanism that enables rapid path selection. The convergence time is also minimized (5.3 s), highlighting the algorithm's fast stabilization and suitability for real-time routing environments.

B. Healthcare Sensor Networks

Algorithm	PDR (%)	Delay (ms)	Convergence Time (s)
LEACH	80.2	290	15.1
PEGASIS	82.3	270	14.3
PSO	86.5	250	11.8
CCA	90.4	210	9.5

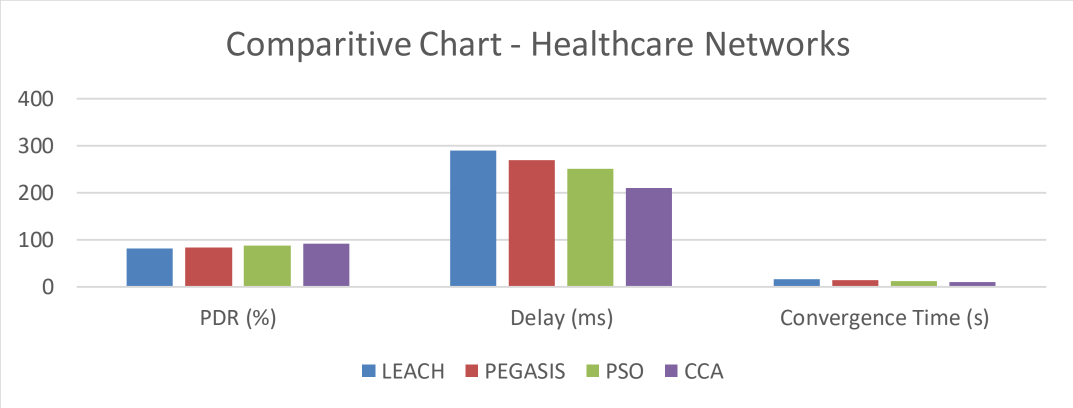

Figure 2 – Health Care Sensor Network Comparison Chart

Figure 2 presents the performance comparison of CCA with conventional clustering and optimization algorithms in healthcare sensor networks modeled in MATLAB. The proposed CCA attains a higher PDR of 90.4%, reflecting improved data reliability and reduced packet loss in energy-constrained medical sensing environments. End-to-end delay is reduced to 210 ms, indicating efficient routing decisions with minimal communication overhead. Furthermore, the faster convergence time (9.5 s) demonstrates CCA's ability to quickly adapt to node dynamics and topology changes, making it well-suited for latency-sensitive healthcare monitoring applications.

C. Robotics & Autonomous Vehicles

Algorithm	PDR (%)	Delay (ms)	Convergence Time (s)
A*	75.5	310	18.3
D*	78.3	295	16.5
RRT	84.2	240	13.2
CCA	89.7	200	10.1

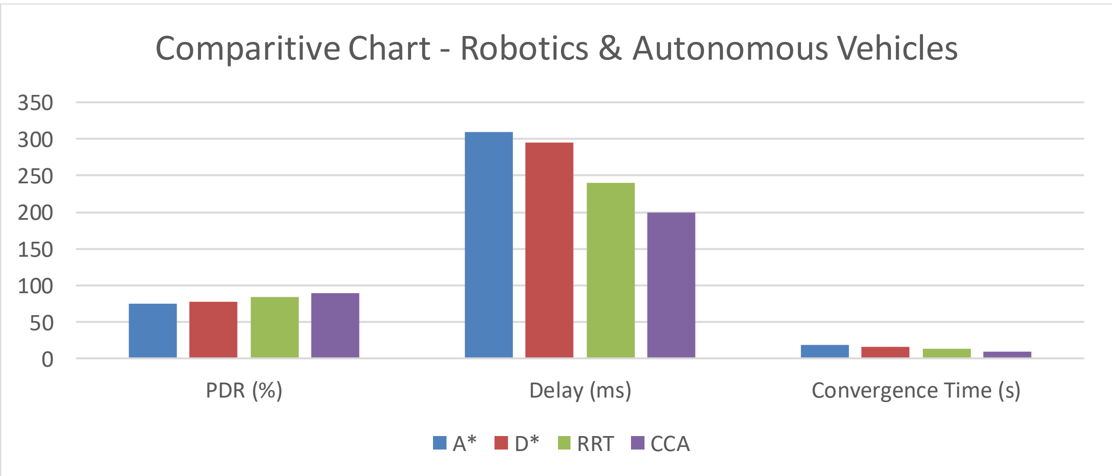

Figure 3 – Robotics and Autonomous Vehicles Comparison Chart

Figure 3 compares the effectiveness of CCA with classical path-planning algorithms such as A*, D*, and RRT in robotics and autonomous vehicle navigation. The results show that CCA achieves a PDR of 89.7%, indicating robust path selection even in dynamically changing environments. The reduction in delay to 200 ms highlights smoother and more efficient trajectory planning. Additionally, CCA converges faster (10.1 s) than traditional planners, validating its ability to rapidly compute optimal paths through its exploration–exploitation balance inspired by cheetah hunting behavior.

D. Supply Chain Logistics

Algorithm	PDR (%)	Delay (ms)	Convergence Time (s)
Greedy	70.6	340	20.1
ACO	74.3	300	17.8
PSO	78.8	280	15.3
CCA	84.1	240	12.7

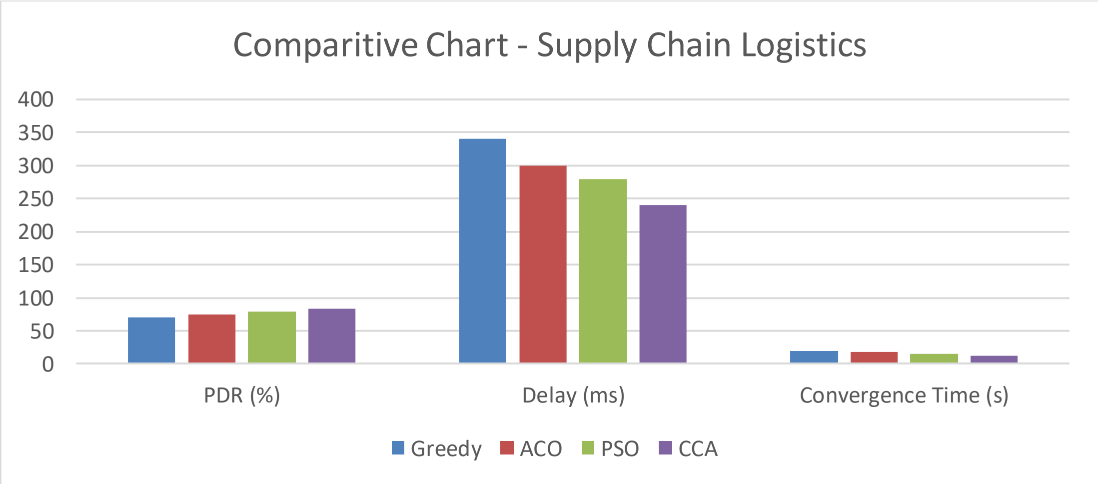

Figure 4 – Supply Chain Logistics Comparison Chart

Figure 4 demonstrates the application of the Cheetah Chase Algorithm in supply chain logistics optimization. Compared to greedy, ACO, and PSO approaches, CCA achieves a notable improvement in PDR (84.1%), indicating higher delivery success rates and reduced routing failures. The end-to-end delay is minimized to 240 ms, reflecting efficient decision-making in route and resource allocation. The convergence time of 12.7 s further confirms that CCA efficiently scales to complex logistics networks, enabling timely optimization in large-scale and time-critical supply chain operations.

E. VANETs

Algorithm	PDR (%)	Delay (ms)	Convergence Time (s)
GPSR	82.5	250	13.0
GYTAR	85.1	230	11.5
PSO	88.3	200	10.2
CCA	91.7	165	7.8

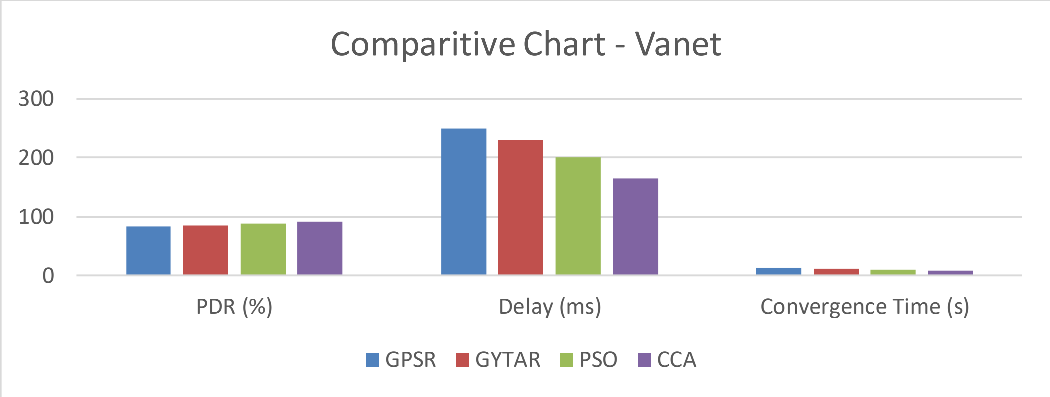

Figure 5 – Vanet Comparison Chart

Figure 5 illustrates the performance evaluation of CCA in Vehicular Ad Hoc Networks (VANETs) using NS-3 simulations. The proposed algorithm outperforms GPSR, GYTAR, and PSO by achieving the highest PDR (91.7%), ensuring reliable data delivery in highly mobile vehicular environments. A significant reduction in end-to-end delay (165 ms) is observed, attributed to CCA's rapid response to frequent topology changes. Moreover, the reduced convergence time (7.8 s) highlights its effectiveness in fast-changing VANET scenarios, making it suitable for intelligent transportation systems.

F. VLSI Design

Algorithm	PDR (%)	Delay (ms)	Convergence Time (s)
Maze Routing	68.4	380	22.3
Line-Probe	72.1	340	20.4
ACO	76.9	310	18.2
CCA	82.3	270	14.9

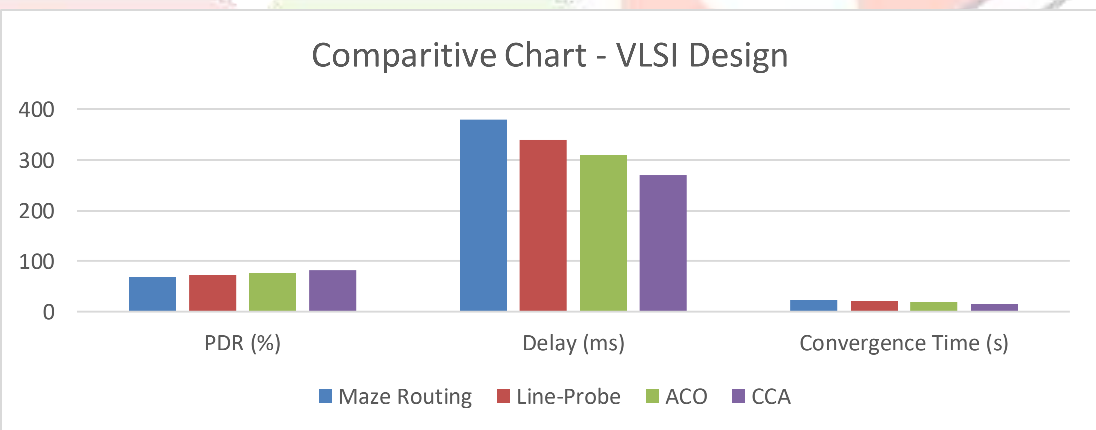

Figure 6 – VLSI Design Comparison Chart

Figure 6 presents a comparative analysis of routing optimization techniques in VLSI design environments using industry-standard EDA tools. The proposed CCA demonstrates superior performance with a PDR of 82.3% and a reduced signal delay of 270 ms, indicating improved routing efficiency and lower interconnect latency. Compared to maze routing, line-probe, and ACO methods, CCA achieves faster convergence (14.9 s), which can be attributed to its adaptive acceleration and intelligent path refinement strategy. These results validate the applicability of CCA for timing-critical and large-scale VLSI routing optimization.

5. Conclusion

The Cheetah Chase Algorithm exhibits remarkable versatility and effectiveness across diverse real-world optimization scenarios. Its biologically inspired pursuit model provides fast and intelligent decision-making, while its modular structure makes it adaptable to hybrid enhancements using fuzzy logic or neural networks. As technology evolves, CCA stands as a powerful optimization strategy for autonomous systems, smart infrastructure, and high-performance computing environments.

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