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MOSMA: Multi-Objective Slime Mould Algorithm Based on Elitist Non-Dominated Sorting

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ABSTRACT This paper proposes a multi-objective Slime Mould Algorithm (MOSMA), a multi-objective variant of the recently-developed Slime Mould Algorithm (SMA) for handling the multi-objective optimization problems in industries. Recently, for handling optimization problems, several meta-heuristic and evolutionary optimization techniques have been suggested for the optimization community. These methods tend to suffer from low-quality solutions when evaluating multi-objective optimization (MOO) problems than addressing the objective functions of identifying Pareto optimal solutions' accurate estimation and increasing the distribution throughout all objectives. The SMA method follows the logic gained from the oscillation behaviors of slime mould in the laboratory experiments. The SMA algorithm shows a powerful performance compared to other well-established methods, and it is designed by incorporating the optimal food path using the positive-negative feedback system. The proposed MOSMA algorithm employs the same underlying SMA mechanisms for convergence combined with an elitist non-dominated sorting approach to estimate Pareto optimal solutions. As a posteriori method, the multi-objective formulation is maintained in the MOSMA, and a crowding distance operator is utilized to ensure increasing the coverage of optimal solutions across all objectives. To verify and validate the performance of MOSMA, 41 different case studies, including unconstrained, constrained, and real-world engineering design problems are considered. The performance of the MOSMA is compared with Multiobjective Symbiotic-Organism Search (MOSOS), Multi-objective Evolutionary Algorithm Based on Decomposition (MOEA/D), and Multiobjective Water-Cycle Algorithm (MOWCA) in terms of different performance metrics, such as Generational Distance (GD), Inverted Generational Distance (IGD), Maximum Spread (MS), Spacing, and Run-time. The simulation results demonstrated the superiority of the proposed algorithm in realizing high-quality solutions to all multi-objective problems, including linear, nonlinear, continuous, and discrete Pareto optimal front. The results indicate the effectiveness of the proposed algorithm in solving complicated multi-objective problems. This research will be backed up with extra online service and guidance for the paper's source code at <https://premkumarmanoharan.wixsite.com/mysite> and <https://aliasgharheidari.com/SMA.html>. Also, the source code of SMA is shared with the public at <https://aliasgharheidari.com/SMA.html>.

INDEX TERMS Constrained, multi-objective optimization problems, multi-objective slime mould algorithm (MOSMA), real-world problems, slime mould algorithm (SMA), unconstrained.

I. INTRODUCTION

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In any real-world case, a large set of solutions need to be determined precisely and estimated to minimize

(or maximize) several objectives at hand. Such problems often happen when we need to advance a decision-making model [1], [2]. These kinds of models and instances are not only limited to function optimization, but practitioners face them in any discipline, especially fuzzy optimization [3], location-based services [4], traffic management [5], neural networks [6], wireless sensor networks [7]–[9], honeynet potency [10], monitoring [11], [12], computer-aided design [13], and Internet of things [14]. Real-world engineering design problems require optimization algorithms to be utilized and find the best possible solutions [3]. Optimization problems appear in many fields, and in most real-world cases, it is required to optimize several objectives together [15]. These problems can be multi-objective [16] or later; they can have many objective forms [17], [18]. Before the popularity of computers, researchers used to make many trials and errors to find optimal solutions for such problems. Human involvement was essential but compromised the accuracy of the overall problem-solving process. Using computers to automate this process has always been a priority to mitigate manual optimization and design risk. In the area of computer-aided design [13], [19], [20], computers assist practitioners in solving optimization problems. Therefore, designers need to focus on the setup and preparation of the problem more than the optimization process itself. This way of problem-solving is inherently faster and less prone to human errors. However, preparing the problem in a format readable and solvable by the machine requires relevant expertise.

In the optimization field, algorithms are designed and developed as 'recipes' for computers to solve problems [21]. They can be divided into two classes: deterministic [1] and stochastic [23]. Deterministic methods find the same solution in each run but suffer from trapping in locally optimal solutions. However, stochastic approaches find different solutions in each run due to the use of stochastic mechanisms. This assists them in avoiding sub-optimal solutions better. Most heuristic and meta-heuristics algorithms belong to the latter class. It is possible to generally classify meta-heuristic optimization methods into two types, such as single-objective and multi-objective. Single-objective methods aim to provide an optimal solution after improving the primary objective function. Some of the well-regarded algorithms are Genetic Algorithm (GA) [42], Differential Evolution (DE) [22], Particle Swarm Optimization (PSO) [48], Whale optimizer algorithm with Nelder-Mead [23], Harris hawks optimization algorithm with Nelder-Mead [24], spotted hyena optimization [25], Seagull optimization algorithm [26], Henry gas solubility optimization algorithm [27], Mine blast algorithm [28], and Butterfly optimization [29].

The algorithms mentioned above can estimate the global optimum for the optimization problem considering one objective. However, in a wide range of real-world problems, multiple objectives should be optimized simultaneously, often in conflict [30]. The sub-field of evolutionary computation to solve such problems is called Evolutionary Multi-Objective Optimization (EMOO) [31], which deals with the philosophy

and submissions of multi-objective evolutionary algorithms [30]–[32]. Some of the most popular algorithms in EMOO are the Non-dominated Sorting Genetic Algorithm (NSGA) [44], Multi-objective PSO (MOPSO) [49], and Multi-objective Evolutionary Algorithm based on Decomposition (MOEA/D) [67]. Multi-objective EMOO algorithms can be divided into three classes based on decision-makers' involvement: a priori, posteriori, and interactive. In a priori method, a decision-maker provides us with preferences, and we can use them to combine the objectives into a single one. So, a single objective algorithm can be used in this case. In a posteriori algorithm, decision making is done after completing the optimization process. So, an algorithm finds a sub-set of Pareto optimal solutions for decision-makers. Finally, in an interactive method, decision-makers are involved during the optimization process. Multi-objective optimization (MOO) does not have a single solution, and many convergences among the different objectives. The reality that Pareto fronts (PF) have to come up with numerous points for good theories on the PF is particularly dreadful to every MOO problem [35]. Even still, it is not predicted that the MOO strategies on the PF are uniformly distributed on the front [36]. It is also tough to predict the solution to such multi-dimensional issues.

A well-known principle, called No Free Lunch theory, has claimed in this regard that there is no single algorithm to solve optimization problems altogether [33]. Because of this principle, there is no assurance that an optimization algorithm has the same efficiency in different problems. According to this fact, the multi-objective variant of a newer algorithm is being created, which has exciting results based on evolutionary computation compared to the state-of-the-art techniques. This work focuses on a posteriori algorithm by proposing the multi-objective version of a recently-proposed metaheuristic called Slime Mould Optimizer (SMA)¹ algorithm [34]. The algorithm is called Multiobjective SMA (MOSMA), which is designed using non-dominated sorting and crowding distance mechanisms. The proposed MOSMA is a popular MOO algorithm that consists of a random search with good search capabilities, a non-dominant sort maintains Pareto dominance, and a crowding distance increases the solution's diversity. The key contributions to this study can be summarized as follows.

- An archive component is applied to the basic version of SMA that can store all non-dominated Pareto solutions.
- The non-dominated sorting and the crowding distance mechanism is applied to handle the Pareto dominance and the solution diversity.
- The validity of MOSMA is verified for 41 case studies, including real-world engineering design optimization problems.
- The performance indicators are listed for all case studies to prove the effectiveness of the MOSMA.

The rest of the paper is planned as follows: Section 2 describes the structure of the multi-objective optimization

¹<https://aliasgharheidari.com/SMA.html>

problems with its basic definitions and the related works in solving MOO problems. Section 3 presents the basic version of SMA and proposes the MOSMA algorithm. Section 4 represents the results/discussions/analysis of the proposed SMA. As a final point, Section 5 provides the conclusion of the work and future directions.

II. RELATED WORKS AND LITERATURE REVIEW

This section first introduces basic terminologies of MOO problems and their basic definitions, such as Pareto optimality, Pareto dominancy, Pareto optimality set, and Pareto optimality front. Further, the related works in solving MOO problems are discussed in detail.

A. MULTI-OBJECTIVE OPTIMIZATION

The structure of the multi-objective optimization problems can be represented as a maximization/minimization problem as follows:

$$\begin{aligned} \text{Min } & F(\vec{x}) = \{f_1(\vec{x}), f_2(\vec{x}), \dots, f_o(\vec{x})\} \\ \text{Max } & \\ \text{Subject to: } & g_i(\vec{x}) \geq 0, \quad i = 1, 2, \dots, m \\ & h_i(\vec{x}) = 0, \quad i = 1, 2, \dots, p \\ & Lb_i \leq x_i \leq Ub_i, \quad i = 1, 2, \dots, n \end{aligned} \quad (1)$$

where n represent the number of design variables, o represents the number of objective functions, m represents the number of inequality constraints, p represents the number of equality constraints, g_i represent i^{th} inequality constraints, h_i indicates the i^{th} equality constraints, and $[Lb_i, Ub_i]$ represents the i^{th} variable's lower & upper boundaries. Relational operators are no longer adequate for comparing solutions to a problem with multiple objectives. In this case, a new operator called Pareto optimality is used. The essential definitions in this regard are as follows:

Definition 1 (Pareto Dominance [35]):

Assume two vectors such as: $\vec{x} = (x_1, x_2, \dots, x_k)$ and $\vec{y} = (y_1, y_2, \dots, y_k)$. The vector \vec{x} is said to dominate the vector \vec{y} (denoted as $\vec{x} \prec \vec{y}$), if and only if:

$$\forall i \in \{1, 2, \dots, k\} : f_i(\vec{x}) \leq f_i(\vec{y}) \wedge \exists i \in \{1, 2, \dots, k\} : f_i(\vec{x}) < f_i(\vec{y}) \quad (2)$$

Definition 2 (Pareto Optimality [35]):

A solution $\vec{x} \in X$ is called Pareto-optimum if and only if:

$$\nexists \vec{y} \in X | F(\vec{y}) \prec F(\vec{x}) \quad (3)$$

Definition 3 (Pareto optimal set [35]):

The set of all Pareto-optimal solutions is called the Pareto set as follows:

$$P_s = \{x, y \in X | \exists F(\vec{y}) \succ F(\vec{x})\} \quad (4)$$

Definition 4 (Pareto optimal front: A set containing the value of objective functions for Pareto solutions set [35]):

$$P_f = \{F(\vec{x}) | \vec{x} \in P_s\} \quad (5)$$

For solving a MOO problem using a posteriori method, we have to catch the Pareto optimal set. This set is the group of solutions on behalf of the Grade A trade-offs among objectives. This is illustrated in Fig. 1, in which the parametric space and objective space are visualized. The image of two solutions in both spaces is compared that clearly shows the circle is a better solution than the rectangle since it dominated the rectangle considering all objectives.

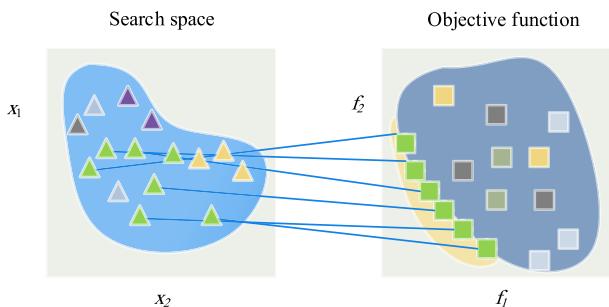


FIGURE 1. Parameter space and objective space in multi-objective optimization.

B. RELATED WORKS

A multi-objective optimization methodology was introduced to evolutionary algorithms by Schaffer in 1984. The idea behind this was to use Pareto dominance operators, and optimum Pareto set instead of relational operators that give a single optimum solution. In the area of EMOO's famous multi-objective optimizers, the literature is MOEA/D, NSGA-II, MOPSO, Pareto Archived Evolutionary [36], and Prato-frontier Differential Evolution (PDE) [37]. As discussed above, such algorithms are divided into three classes: aggregation (*a priori*) method [38], *a posteriori* method [39], and interactive methods [40].

In aggregation-based, multi-objective problems can be converted into single optimization using different weights assigned to objectives. After converting the problem into one objective, an optimal solution can be found using a single-objective algorithm. The main advantage of *a priori* methods is that they do not require modifications in the algorithm. However, the disadvantage of *a priori* methods is the applicability to only convex parts failure in finding Pareto optimal solution in non-convex regions of the Pareto fronts [35]. There are several improvements in such techniques (e.g. [40]), but similar issues still exist. On the other hand, a posteriori approach does not need to convert the multi-objective problem into a single objective instead of an *a priori* approach. Such optimizers can get Pareto optimal front and solutions in one run, but they have to address multiple, often in conflict, objectives.

From detailed literature, it is observed that priori methods are faced with specific problems in tackling multi-objective difficulties, trapped in local optima, having high computational time, and problems emerging from priori method structures [41]. As a result of the initiative to establish various

approaches, Posteriori approaches have been developed. The multi-objective meta-heuristic algorithms (MOMHAs) are among the posteriori techniques, and it has an essential feature, such as reduced computing time and good results irrespective of the nature of the problem. Each candidate solution produces a reliable solution based on its closeness to PF and the spread (diversity) on PF while analyzing the MOO problems with MOMHAs. Throughout the evaluation of parents and the choice of the solutions that survive, such results are used. For counting, there are three fundamental methods used [40]:

- Pareto-based
- Indicator-based
- Decomposition-based

Pareto-based - Goldberg [42] first suggested in 1989, it was possible to use the Pareto-dominance principle to evaluate the optimal solution. Many MOMHAs also introduced several frameworks, motivated by this concept, that uses the Pareto-dominance principle to rate the proximity of optimal PF solution. For instance, Deb *et al.* rated the optimal solution using NSGA-II non-dominated-ranking mechanism [43, 44]. Multi-objective Seagull Optimization Algorithm [45], MOEAs [46], NSGA-III [47], bare-bones multi-objective particle swarm optimization [48], MOPSO [49], multi-swarm cooperative multi-objective particle swarm optimizer [50], MOWCA [51], incremental learning hybridized with adaptive differential evolution [52], MOSOS [53], and cooperative co-evolutionary optimization [54] are among the well-known Pareto-based MOMHAs in the literary works.

Indicator-based - A large number of quality metrics have been reported in the literature to measure the degree to which in terms of convergence and distribution, the PF achieved by a MOMHA for a problem shows the entire PF. A few of the indicators only measure the convergence performance (GD [53], etc.) or the diversity (Spacing [53], Spread [53], etc. of the PF collected, while others improve the impact of both convergence and diversity (Hyper Volume (HV) [54], IGD [55], etc.).

Decomposition-based - A Pareto-optimal response may be an appropriate choice to a scalar function obtained by integrating all of a multi-objective optimization problem's cost function. Therefore, a Pareto-optimal front can be broken down into various scalar optimization problems [54]. To enhance the decomposed fitness function created by the same weight vectors, decomposition-based strategies use this basic principle. Many decomposition-based algorithms are reported, and the following are the three optimizers adopting the proposed MOEA/D [67], MOMH/D [55], decomposition-based archiving approach [56], and Dynamic interval multi-objective optimization problems [57]. Therefore, in this work, a posteriori approach is applied in the SMA algorithm based on the elitist non-dominated approach similar to NSGA-II.

The next section first signifies the model of the SMA technique. Then, the novel multi-objective SMA is developed in this research.

III. MULTIOBJECTIVE SLIME MOULD ALGORITHM (MOSMA)

A. SLIME-MOULD ALGORITHM

The Slime Mould Algorithm [34] (SMA), proposed by Li *et al.* (2020), is a novel population-based metaheuristic inspired by the oscillation behaviors of slime mould in nature. The SMA algorithm is designed by incorporating the optimal food path using the positive-negative feedback system. According to the quality of food slime mould dynamically adjust their search path. The SMA algorithm mimics three fundamental principles, such as grapple, wrap, and approach phenomena. The grapple phenomena that avoid the collision among the slime mould while hunting for food. The wrap phenomena show the velocity matching of slime mould. Moreover, the approach phenomena, which states the learning of slime mould towards the food centre.

The SMA approach starts with a randomly generated population within its upper and lower boundary, where 'N' population size (i.e., slime mould) and 'dim' is the dimension of a problem. Next, the population is evaluated using an objective function. In the following stage, the population is updated by grabbing, wrapping, and approaching phenomena in each iteration. Moreover, the SMA algorithm's progression is controlled by various parameters such as fitness weight (W) of slime mould that can provide faster convergence and avoid local solutions. The vibration parameter (V_b) ensures early exploration or later exploitation accuracy of individual slime mould. The detailed stepwise process of the SMA algorithm, which includes grabbing food, wrap food, and approach food, which can be mathematically detailed as below [34]:

$$\begin{cases} \vec{X}^* = rand \cdot (Ub - Lb) + Lb, & \text{if } (rand < 0.03) \\ \vec{X}^* = \vec{X}_b(t) + \vec{vb} \\ \cdot (W \cdot \vec{X}_A(t) - \vec{X}_B(t)), & \text{if } (r < p) \\ \vec{X}^* = \vec{vc} \cdot \vec{X}(t), & \text{if } (r \geq p) \end{cases} \quad (6)$$

where,

$$\begin{cases} \overrightarrow{W(SmellIndex(i))} \\ = \left\{ \begin{array}{l} 1 + r \cdot \log \left(\frac{bF - S(i)}{bF - wF} + 1 \right), \quad \text{condition} \\ 1 - r \cdot \log \left(\frac{bF - S(i)}{bF - wF} + 1 \right), \quad \text{others} \end{array} \right. \\ SmellIndex = sort(S) \\ \vec{vb} = [-a, a] \\ a = \text{arctanh} \left(- \left(\frac{t}{Max_t} \right) + 1 \right) \\ p = \tanh |S(i) - DF| \end{cases} \quad (7)$$

where \vec{vb} is vibration parameter, t represents the current iteration, \vec{X} represents the location of slime mould, \vec{W} represents the weight of slime mould. DF represents the best fitness obtained in all iterations, $S(i)$ ranks first half of the population, r denotes the random value in the interval of $[0, 1]$, bF denotes the optimal, wF denotes the worst fitness, $SmellIndex$ denotes the sequence of fitness values sorted (ascends in the

minimum value problem, Lb and Ub denote the lower and upper boundaries of the search range, $rand$ and r denote the random value in $[0,1]$. The vibration parameter v_b and fitness weight \bar{W} balances between exploration and exploitation. The procedure of the SMA is given in *Algorithm-I*.

Algorithm 1 Pseudocode of SMA

```

Initialize the parameters population size and Maximum number of iterations
Initialize the positions of slime mould,  $X_i(i = 1, 2, \dots, n)$ ;
While ( $t \leq \text{UMax\_t}$ )
  Calculate the fitness of all slime mould
  Update best fitness,  $X_b$ 
  Calculate the  $W$  by Eq.(7);
  For each search portion
    Update  $p, vb, vc$ ;
    Update positions by Eq.(6);
  End For
   $t = t + 1$ ;
End While
Return the best fitness,  $X_b$ 
  
```

A detailed description of the SMA algorithm is given in Fig. 2. In the SMA optimizer's leading paper, it has been proved that this algorithm solves different real-world problems effectively and is competitive compared to the existing algorithms. This motivated us to design a new multiple-objective version of the slime mould optimizer in the following subsection.

B. MULTI-OBJECTIVE SLIME MOULD ALGORITHM (MOSMA)

The proposed MOSMA algorithm uses an elitist non-dominated sorting and a diversity preserving crowding distance mechanism [36]. Non-dominated sorting includes the following steps:

- First, calculating the non-dominated solution
- Second, applying non-dominated sorting (NDS)
- Calculating non-dominated ranking (NDR) of all non-dominated solutions.

Fig. 3 presents the non-domination ranking (NDR) process, in which two fronts are given. The solutions in the first front give the index of 0 since they are not dominated by any solutions, while the solutions in the second front are dominated by at least one of the solutions in the first front. Such solutions' NDR is equal to the number of solutions that dominate them. The crowding distance mechanism is shown in Fig. 4 used to maintain diversity among the acquired solutions. Crowding distance (CD) as follows.

$$CD_j^i = \frac{f_j^{i+1} - f_j^{i-1}}{f_j^{\max} - f_j^{\min}} \quad (8)$$

where, f_j^{\min} and f_j^{\max} are the minimum and maximum values of j^{th} objective function. The schematic representation of a non-dominated sorting-based algorithm is depicted in Fig. 5.

The pseudocode of MOSMA is shown in *Algorithm-II*. Firstly, the algorithm starts with defining the controlling parameters, including search agent/population size (N_{pop}), loop terminated criteria, and maximum iteration/maximum number of generation (Max_t) to run the MOSMA algorithm. Secondly, a random generated parent's population P_o in feasible search space region S is generated, and every objective function of the objective space vector F for P_o is evaluated. Thirdly, the elitist-based *NDS* and *CD* are applied to P_o . Fourthly, a new population of P_j , is created and merged with P_o to get population P_i . This P_i is sorted based on elitism non-domination and the resulted data of *NDR* and *CD*. The best N_{pop} solutions are revised to create a new parent population. Finally, this process is repeated until the end condition is met. The flowchart of MOSMA is depicted in Fig. 6.

Algorithm 2 Pseudocode of MOSMA

Step I	Initially Generate population (P_o) randomly in solution space (S)
Step II	Evaluate objective space (F) for the generated population (P_o)
Step III	Sort the based on the elitist non-dominated sort method and find the non-dominated rank (NDR) and fronts
Step IV	Compute crowding distance (CD) for each front
Step V	Update solutions (P_j) using Algorithm-I
Step VI	Merge P_o and P_j to create $P_i=P_oUP_j$
Step VII	For P_i perform Step II
Step VIII	Based on <i>NDR</i> and <i>CD</i> sort P_i
Step IX	Replace P_o with P_i for N_{pop} first members of P_i

C. COMPUTATION COMPLEXITY OF MOSMA

The computation complexity of the proposed MOSMA is given in terms of space complexity and time complexity. As discussed earlier, the proposed MOSMA uses the same operators of NSGA-II. Since the NDS and CD assignment of MOSMA are adopted from NSGA-II, the computational space complexity of MOSMA is $O(MN_{pop}^2)$, where M is the total number of objective functions, and N_{pop} is the number of search agents/population size. The computational time complexity of the MOSMA is presented for each iteration. For the first iteration, the computational time complexity is equal to $O(dim*N_{pop} + Cost(f_{obj})*N_{pop})$. After the first iteration, the computational time complexity is equal to $O(dim*N_{pop} + Cost(f_{obj})*N_{pop} + (NDS+CD)*dim)$. In addition, the overall computational time complexity of the MOSMA is given for the maximum number of iteration which is equal to $time=O(M)|M=(dim*Max_t*N_{pop} + Cost(f_{obj})*Max_t*N_{pop} + (NDS+CD)*(Max_t-t)*dim + (NDS+CD)*(Max_t-t)*Cost(f_{obj}))$. Where, current iteration is denoted as t , maximum number of iterations is denoted as Max_t , the objective function is represented by f_{obj} , cost of the

Step I: Provide the input Data

No of Search Agent(N), No of decision variable(dim), lower boundary (Lb), upper boundary (Ub), objective function (fobj), and Maximum Iteration (Max_t)

Step II: Initialize the set of random solutions

```
X=rand(N,dim)*(Ub-Lb)+Lb;
```

Step III: Main Optimization loop start

```
while t <= Max_t
```

Step IV: Check if solutions go outside the search space bring them back

```
AllFitness = fobj(Lb < X > Ub);
```

Step V: Sort the calculated fitness

```
[SmellOrder,SmellIndex] = sort(AllFitness);
worstFitness = SmellOrder(N); bestFitness = SmellOrder(1);
S=bestFitness-worstFitness+eps;
```

Step VI: Update the best fitness value and best position

```
if bestFitness < Destination_fitness
    bestPositions=X(SmellIndex);
    Destination_fitness = bestFitness;
end if
```

```
a = atanh(-(t/Max_t)+1); b = 1-t/Max_t;
```

Step VII: Update the Position of search agents

```
for each search portion
```

Step VIII: Calculate the fitness weight of each slime mould (Wrap Food)

```
if rand()<=half search portion
    weight=1+rand()*log10((bestFitness-smellOrder)/(S)+1);
else
    weight = 1-rand()*log10((bestFitness-SmellOrder)/(S)+1);
end if
if rand<0.03
    X=(Ub-Lb)*rand+Lb;
else
    p=tanh(abs(AllFitness - Destination_fitness));
    vb=unifrnd(-a,a,1,dim); (Grapple Food)
    vc=unifrnd(-b,b,1,dim); r=rand();
```

Step IX: Two positions randomly select from search agent (Approach Food)

```
A = randi([1,N]);
B = randi([1,N]);
if r<p
    X=bestPositions+vb*(weight*X(A)-X(B));
else
    X=vc*X;
end if
end if
end for
t=t+1;
end while
```

Step X: Return Destination_fitness (P_j)

FIGURE 2. Step by step approach of the slime-mould optimizer.

objective function is denoted as $Cost(f_{obj})$, and the number of variables in objective function is denoted as dim .

IV. RESULTS AND DISCUSSIONS

In this section, the performance validation of the proposed MOSMA is discussed. In order to prove the validity of the MOSMA, a comprehensive set of benchmark functions, including constrained, unconstrained, and real-world problems are considered.

A. EXPERIMENTAL SETUP

The case studies used to benchmark the performance of MOSMA are as follows:

- Unconstrained ZDT & CEC-2009 benchmarks with 2-objectives (ZDT1-ZDT4, ZDT6) & (UF1-UF10) [58]–[68].
- Constrained benchmark with 2-objectives (TNK, KITA, CONSTR, OSY & SRN) [69]–[73].

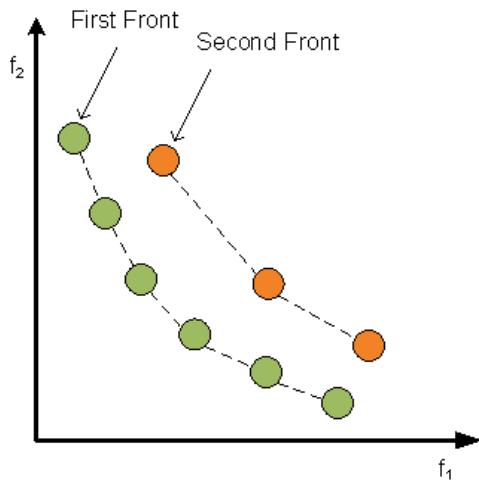


FIGURE 3. Diagram of non-dominated sorting.

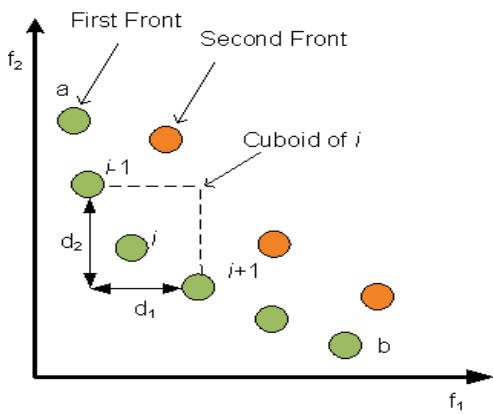


FIGURE 4. Diagram of crowding distance approach.

- Real-world highly nonlinear constraint, discrete, continuous & mix-integer design MOO problems, including 2-bar truss design, 3-bar truss design, 4-bar truss design, disk brake design, CNC machine tool design, discrete-gear train design, bar vessel design, welded beam design, I-beam design, C-beam design, multiple disk clutch brake design, car crash design, car side impact design, metal cutting tool design, rolling element bearing design, helical spring design, satellite heat pipe design, speed reducer design, BLDC motor design, and isolated safety transformer design [74]–[86].

The authors established an environment that ensures fairness, reliability, and justice among the methods we compared to avoid any accidental bias toward a better condition for any algorithm. This condition is a constraint in experiments to ensure that the superiorities are not due to the testing advantages.

In general, the performance of all multi-objective algorithms is measured using the performance indicators. Therefore, to compare the MOSMA with other competitive algorithms, the following performance indicators are

used, and the expressions for the same have been stated in Eq. 9-Eq. 12.

$$GD = \frac{\sqrt{\sum_{i=1}^{no} d_i^2}}{n} \quad (9)$$

$$IGD = \frac{\sqrt{\sum_{i=1}^{nt} (d'_i)^2}}{n} \quad (10)$$

$$\text{Spacing(SP)} \triangleq \sqrt{\frac{1}{n-1} \sum_{i=1}^n (\bar{d} - d_i)^2} \quad (11)$$

$$\text{Maximum Spread (MS)} = \sqrt{\sum_{i=1}^o \max(d(a_i, b_i))} \quad (12)$$

where nt is the number of true Pareto optimal solutions, no is the number of True Pareto optimal set (P_s), d_i and d'_i indicates the Euclidean distance (ED), \bar{d} is the average of all d_i , n is the number of obtained P_s , and $d_i = \min_j (|f_1^i(\vec{x}) - f_1^j(\vec{x})| + |f_2^i(\vec{x}) - f_2^j(\vec{x})|)$ for all $i, j = 1, 2, \dots, n$, o is the number of objectives, a and b is the maximum and minimum value in the i^{th} objective. The first two performance measures quantify the convergence and the last two measures the coverage of Pareto optimal solutions estimated by the algorithms.

B. CONSTRAINT HANDLING APPROACH

Some potential applications of the proposed MOSMA may also have constraints, and they are not limited to landslide prediction, dealing with modelling in the environmental concerns, enhancing the target tracking systems, design of the equipment tracking systems, supply chain management and related multi-objective models, improving the productivity of hydrothermal systems, solving several objectives in order-picking systems, and many applications in the image enhancement, and image segmentation. To solve constrained multi-objective problems, it is needed to put in place a mechanism to avoid violating constraints. This paper uses a static penalty approach to handle constraints in the MOSMA algorithm because its convert constrained problem into an unconstrained problem. In this approach, if any constraint is violated, a large penalty (P_i) is added to the returned objective value. The static penalty function is presented as follows:

$$f_j(X) = f_j(X) + \sum_{i=1}^p P_i \max\{g_i(X), 0\} \\ + \sum_{i=p}^{NC} P_i \max\{|h_i(X)| - \delta, 0\} \quad (13)$$

$f_j(X), j = 1, 2, \dots, n$, (Objective function to be optimized)

$X = \{x_1, x_2, \dots, x_m\}$ are design variables

$g_i(X) \leq 0, i = 1, 2, \dots, p$ are inequality constraints

$h_i(X) = 0, i = p + 1, \dots, NC$ are equality constraints,

δ is tolerance inequality constraint

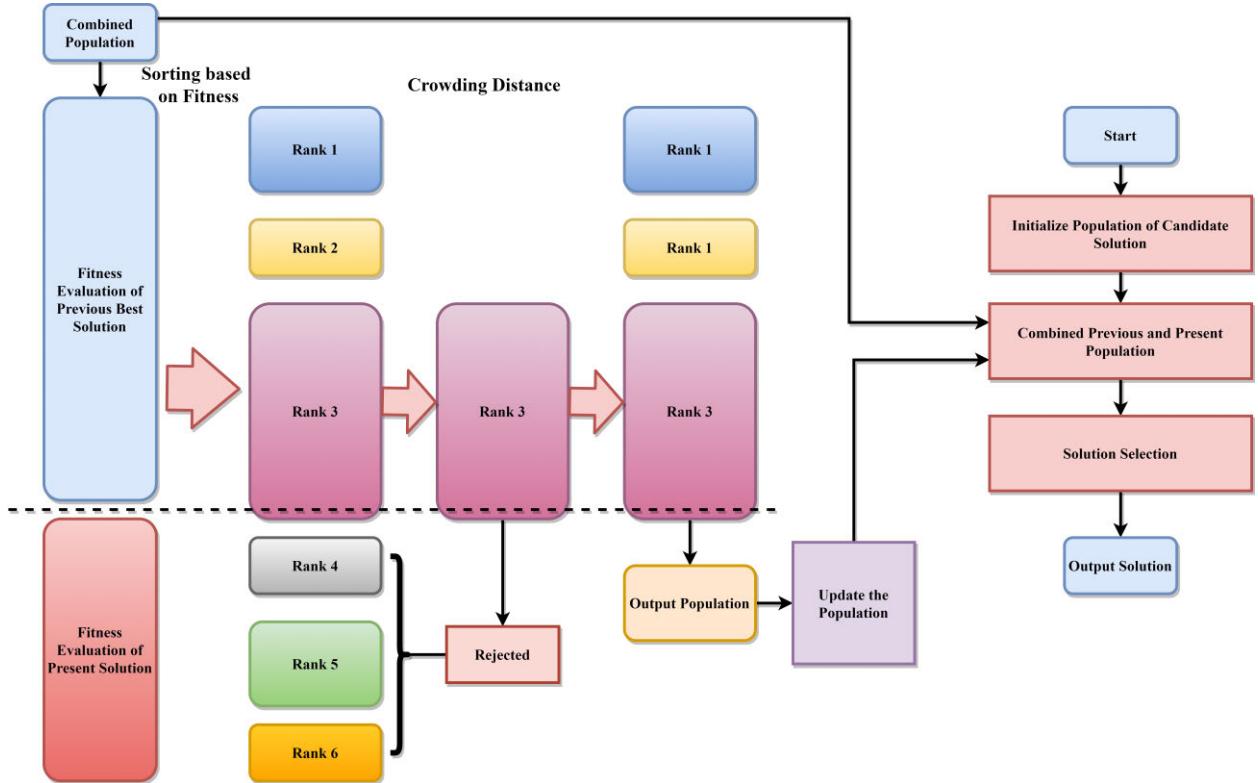


FIGURE 5. Schematic representation of a non-dominated sorting-based algorithm.

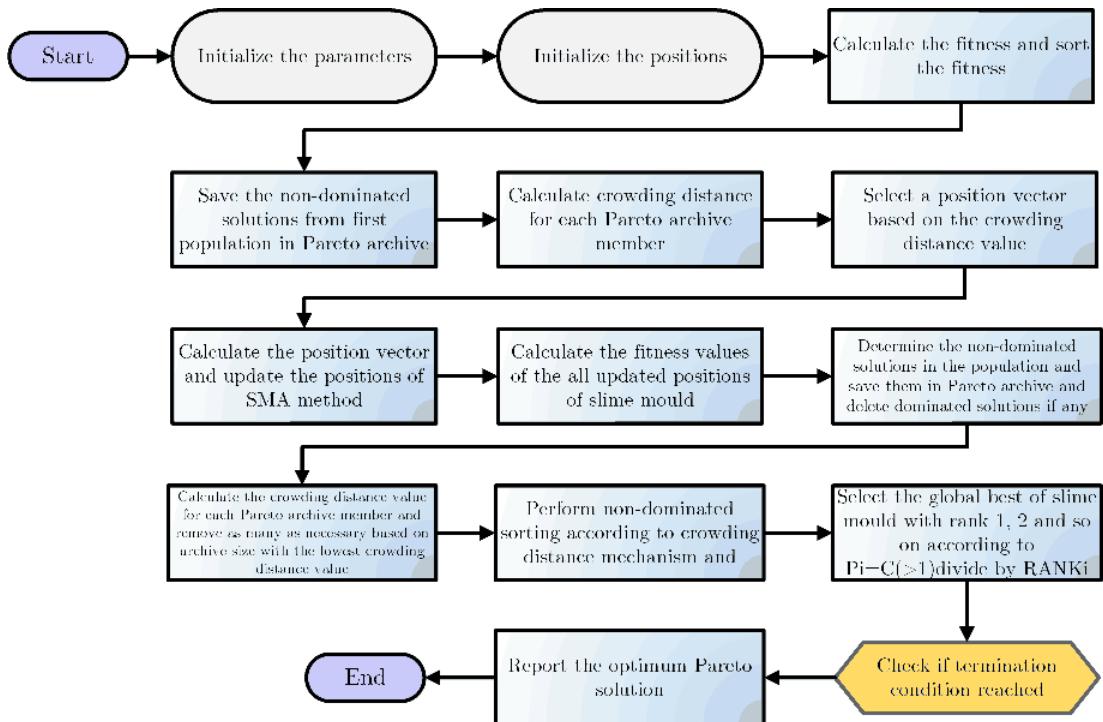


FIGURE 6. Flowchart of Multi-objective SMA.

To observe the outcomes qualitatively, the best Pareto optimal fronts attained by the proposed MOSMA technique on the considered case studies are demonstrated

in Figs. 7 - Fig. 9. The performance of the proposed MOSMA is compared with the other well-known competitive algorithms, such as MOWCA, MOSOS, and

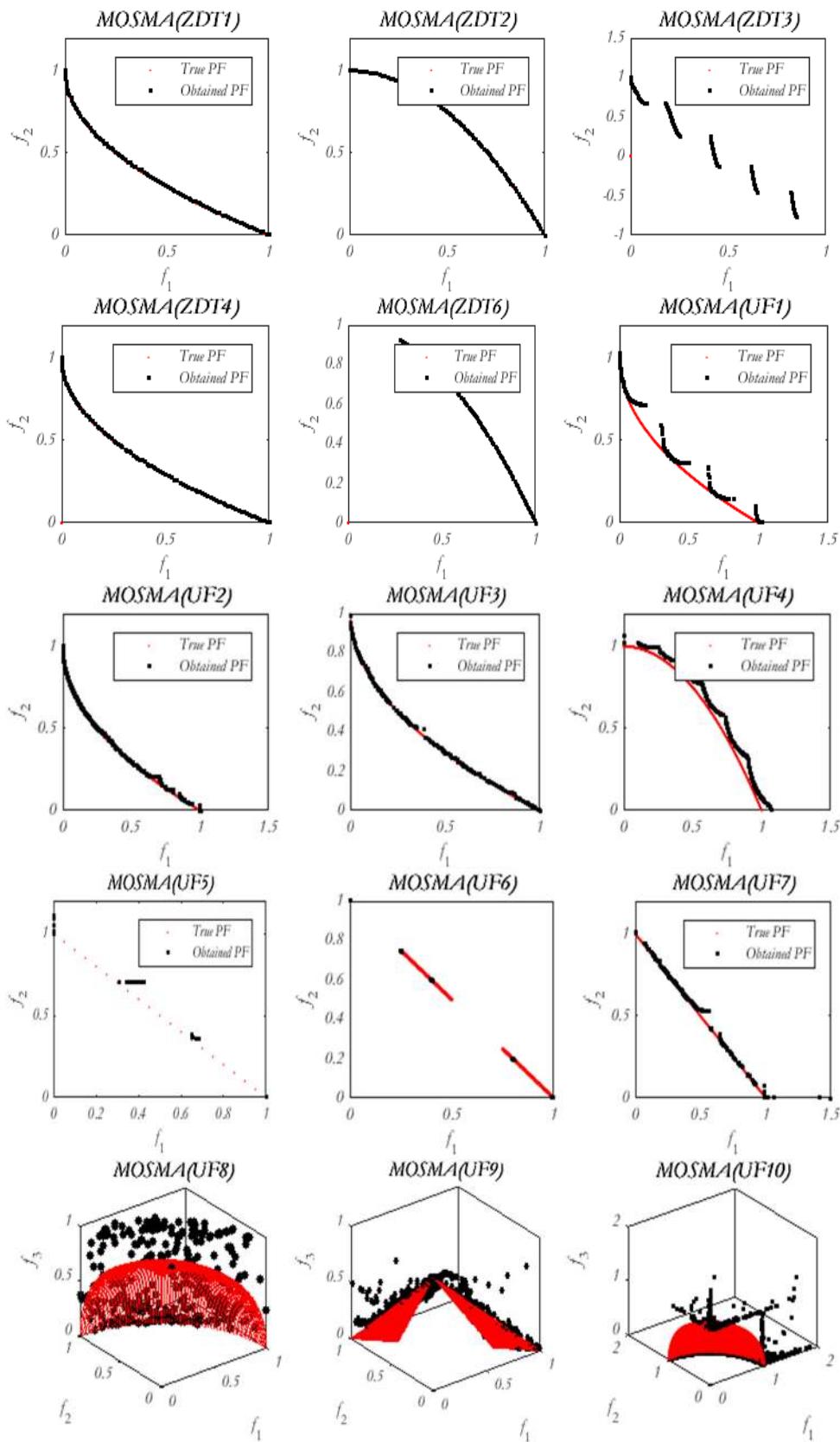


FIGURE 7. Results of Pareto optimal front realized by the MOSMO algorithm on ZDT1, ZDT2, ZDT3, ZDT4, ZDT6, UF1, UF2, UF3, UF4, UF5, UF6, UF7, UF8, UF9, and UF10 cases.

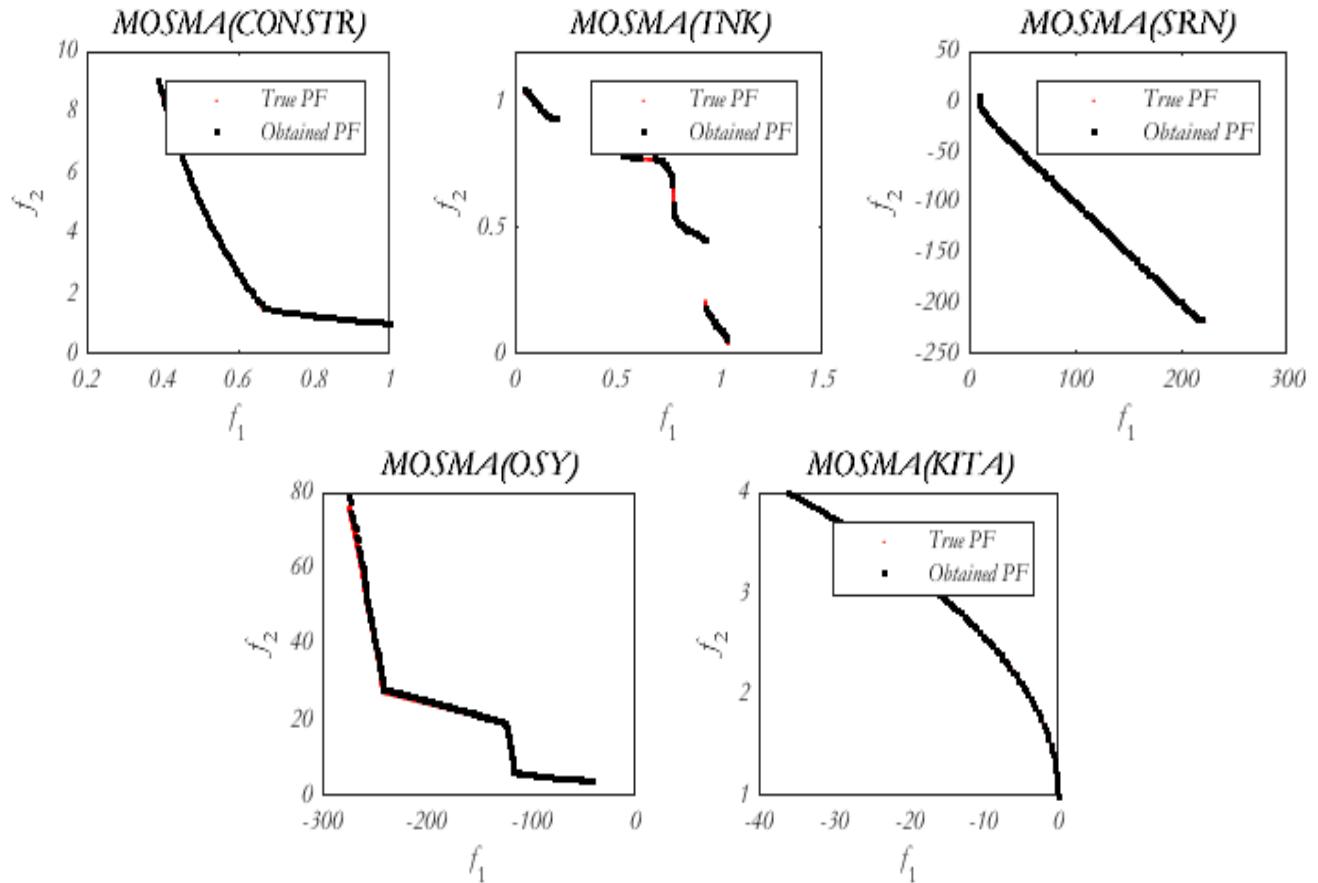


FIGURE 8. Results of Pareto optimal front attained by the MOSMO technique on CONSTR, TNK, SRN, OSY, and KITA benchmark functions.

MOEA/D. The control parameters of all algorithms are listed in Table 1.

C. SIMULATION RESULTS

Based on the non-dominated sorting mechanism to illustrate the effectiveness of the developed MOSMA algorithm, four types of analysis are discussed in this section to evaluate the effectiveness of the MOSMA.

The analysis-I, therefore, aims to evaluate MOSMA optimizer's convergence with MOWCA, MOSOS, and MOEA/D, which all concentrate on enhancing the convergence in the NDS technique. In order to evaluate the convergence output of MOSMA, MOWCA, MOSOS, and MOEA/D concerning GD metrics, the simulation is carried out for 30 individual runs of all algorithms on ZDT1-6, UF1-10 and the constrained benchmark functions, such as TNK, KITA, CONSTR, OSY and SRN, and instead of measuring the mean and standard deviation, the optimal GD (including both mean and standard deviation (SD)) values are listed for all selected problems in Table 2 and Table 7. Boldface highlights the best outcome for each test problem. In Table 2 and Table 7, with more than 78.57% of benchmark functions, the GD value of MOSMA is higher than other algorithms. The GD value of MOSMA has improved 80 % over the other algorithms,

specifically for the ZDT test problem with unimodal, convex, and separable variables.

The purpose of analysis-II is to demonstrate the efficacy of the proposed MOSMA. In order to compare the diversity success of MOSMA, MOWCA, MOSOS, and MOEA/D with respect to Spacing and Spread metrics, the study runs 30 times individually on ZDT1-6, UF1-10, the constrained benchmark functions, such as TNK, KITA, CONSTR, OSY and SRN, and real-world engineering design constrained optimization problems and then found the optimal values of Spacing, Spread. The values are listed in Table 3, Table 4,

Table 8 and Table 9. The value of spacing/spread for the proposed MOSMA is better than other algorithms for more than 79.76 % of all test problems. In fact, MOSMA diversity has increased by 39% relative to MOEA/D and over 36.5% compared to the other two algorithms. The MOSMA Spacing/Spread values are 86.66 %, mostly on UF and constrained design test problems with discrete PF, demonstrating that the MOSMA has a substantial diversity of discrete test problems. It has a uniform solution spread in local PF on ZDT, UF and constrained benchmarks, so it performs well in the Spacing/Spread metric.

Analysis-III aims to demonstrate the robust output of the MOSMA for balancing convergence and diversity compared

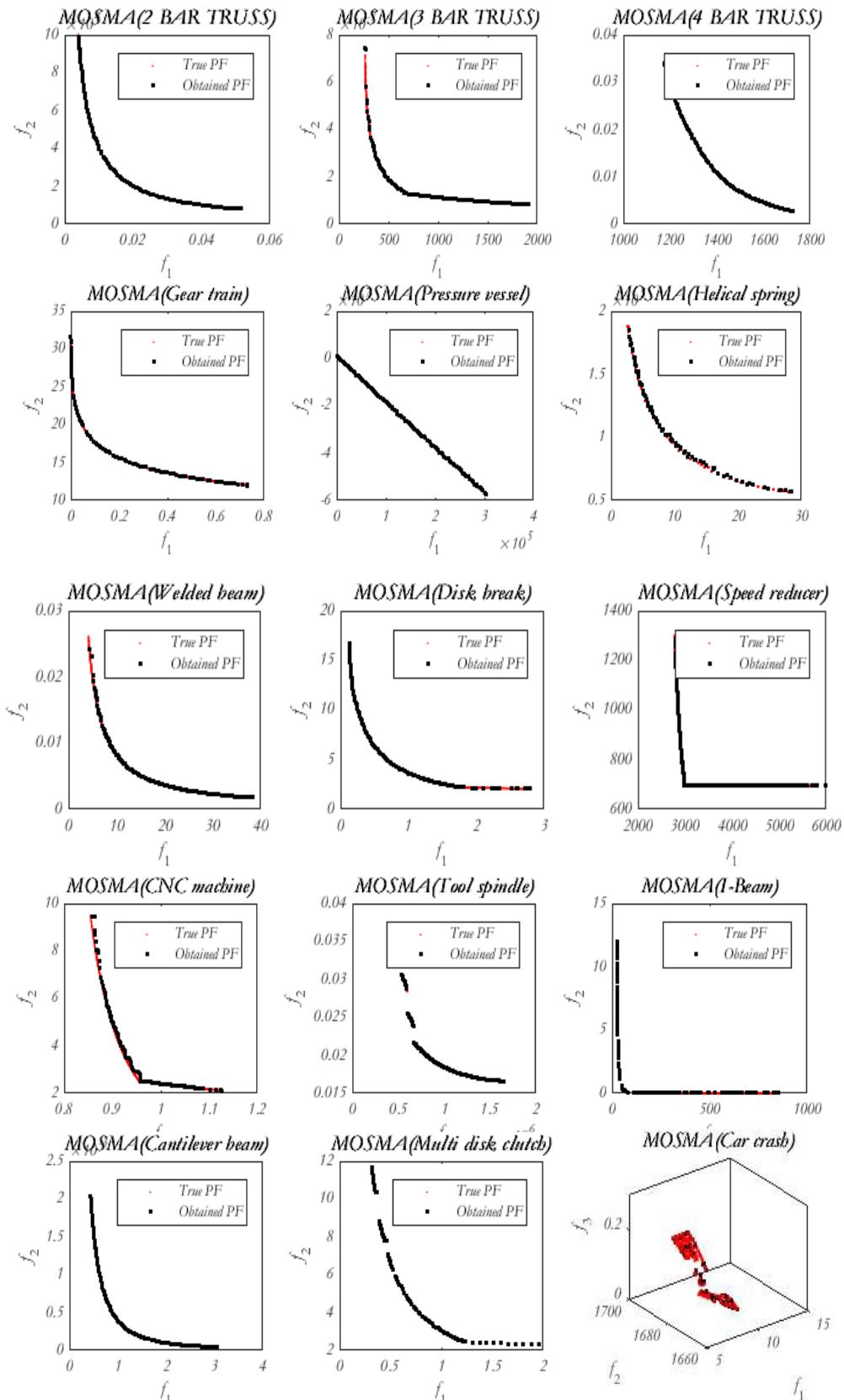


FIGURE 9. Results of Pareto optimal front achieved by the MOSMO method on 2-bar truss, 3-bar truss, 4-bar truss, gear train, pressure vessel, helical spring, welded beam, disk brake, speed reducer, CNC machine tool, tool spindle, I-beam, cantilever beam, multiple disk clutch break, car crash, car side-impact, metal cutting tool, rolling-element bearing, satellite heat pipe, BLDC motor, and isolated safety transformer design problems.

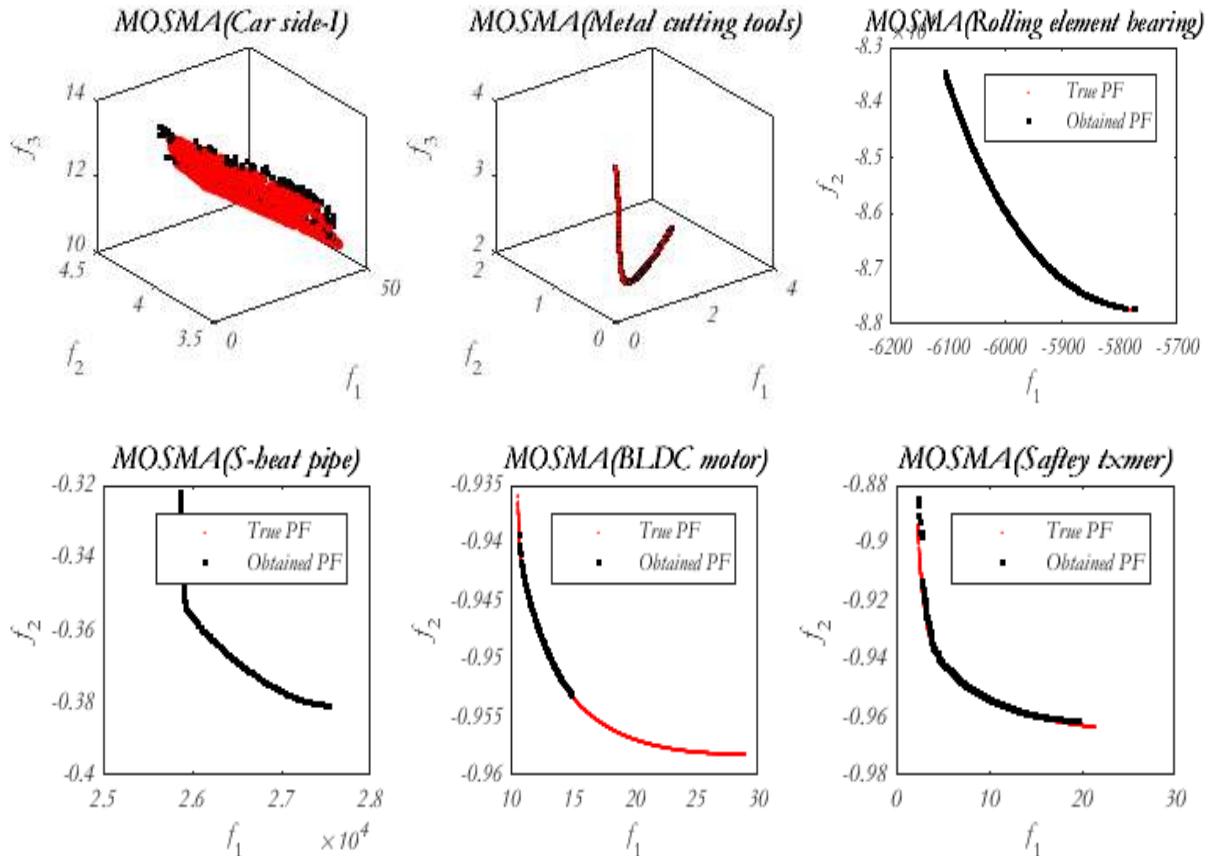


FIGURE 9. (Continued.) Results of Pareto optimal front achieved by the MOSMO method on 2-bar truss, 3-bar truss, 4-bar truss, gear train, pressure vessel, helical spring, welded beam, disk brake, speed reducer, CNC machine tool, tool spindle, I-beam, cantilever beam, multiple disk clutch break, car crash, car side-impact, metal cutting tool, rolling-element bearing, satellite heat pipe, BLDC motor, and isolated safety transformer design problems.

TABLE 1. Control parameters of all algorithms.

Parameters	MOWCA [51]	MOEA/D [67]	MOSOS [69]	MOSMA
Number of Runs	30	30	30	30
Population Size /Search agent (N_{pop})	100	100	100	100
Maximum Number of Iterations (Max_t)	1000	1000	1000	1000
Number of Function Evaluations (FES_{max})	1,00,000	1,00,000	1,00,000	1,00,000
Other Related Parameters	Distribution Index, $\eta = 30$; Crossover Rate, $CR = 0.5$;			
	Number of rivers+sea, $N_{sr} = 4$;			
	Evaporation condition constant, $D_{max}=1e-16$.			
Other Related Parameters	Probability of selecting parents from the neighbourhood, $\delta = 0.9$;			
	Maximal copies of a new child in the update, $n_r = 1$;			
	The number of neighbours, $T = 10$.			

to MOWCA, MOSOS, and MOEA/D. By running 30 times on ZDT1-6, UF1-10, and the constrained benchmark functions, such as TNK, KITA, CONSTR, OSY, and SRN independently, the IGD metric of all algorithms are listed in Table 5 and Table 10. For each algorithm, the best outcomes are displayed in boldface. The IGD metric is used to calculate each algorithm's quantitative efficiency, both considering

convergence, and distribution. Tables 5 and 10 show that the proposed MOSMA ranks first, followed by MOWCA, MOSOS, and MOEA/D.

The purpose of analysis-IV is to demonstrate the efficacy of the proposed MOSMA in terms of run time. In order to compare the time complexity of all algorithms concerning run time metrics, the run time of all algorithms is

TABLE 2. Results of the multi-objective algorithms (using GD) on the selected unconstrained test functions.

Problem	N	M	D	FEs	MOWCA	MOSOS	MOEA/D	MOSMA
ZDT1	100	2	30	100000	8.6012e-5 (9.88e-7)	1.4501e-4 (1.87e-5)	3.3766e-4 (1.02e-4)	6.5167e-5 (4.94e-5)
ZDT2	100	2	30	100000	7.9115e-5 (3.78e-5)	1.0994e-4 (2.01e-6)	2.3756e-4 (7.69e-5)	5.3235e-5 (3.30e-5)
ZDT3	100	2	30	100000	7.0276e-5 (3.44e-5)	6.6463e-5 (1.64e-5)	3.9059e-4 (2.05e-4)	5.5405e-5 (1.47e-5)
ZDT4	100	2	10	100000	3.7541e-2 (1.74e-2)	2.9834e-5 (1.92e-5)	6.6765e+0 (2.60e+0)	2.1453e-5 (1.45e-5)
ZDT6	100	2	10	100000	3.2558e-6 (4.54e-10)	3.6187e-6 (1.10e-7)	9.3319e-3 (1.32e-2)	3.5879e-6 (9.17e-8)
UF1	100	2	30	100000	1.1192e-2 (6.80e-3)	2.8623e-4 (5.63e-7)	4.2068e-3 (5.97e-4)	1.2106e-4 (1.33e-5)
UF2	100	2	30	100000	6.8119e-3 (5.16e-3)	1.7227e-3 (4.84e-5)	4.0264e-3 (8.95e-4)	9.0028e-4 (4.13e-4)
UF3	100	2	30	100000	1.6268e-2 (4.66e-5)	3.4180e-3 (1.72e-3)	1.0230e-2 (2.03e-3)	3.6240e-3 (2.61e-3)
UF4	100	2	30	100000	9.5131e-3 (4.22e-4)	4.8177e-3 (7.55e-5)	7.3641e-3 (7.13e-4)	4.5816e-3 (6.08e-5)
UF5	100	2	30	100000	1.1327e-1 (7.36e-2)	7.1955e-2 (1.07e-2)	1.5841e-1 (6.43e-2)	1.9155e-2 (2.22e-2)
UF6	100	2	30	100000	2.5554e-3 (1.28e-3)	1.7334e-2 (4.61e-3)	4.4733e-2 (8.69e-3)	1.8613e-3 (2.61e-3)
UF7	100	2	30	100000	2.7197e-3 (1.57e-3)	3.7810e-4 (3.94e-4)	1.5920e-3 (5.97e-5)	2.4601e-4 (1.88e-4)
UF8	100	3	30	100000	5.9513e-1 (2.02e-1)	1.1753e-1 (9.12e-2)	2.5970e-1 (5.69e-2)	8.4872e-2 (1.02e-1)
UF9	100	3	30	100000	5.5881e-1 (7.56e-2)	1.4329e-1 (4.02e-2)	4.4996e-1 (6.81e-3)	3.1003e-2 (3.91e-3)
UF10	100	3	30	100000	2.8066e-1 (5.25e-2)	2.9269e-1 (1.85e-1)	4.4664e-1 (1.15e-1)	9.1754e-4 (1.93e-4)

TABLE 3. Results of the multi-objective algorithms (using SPREAD) on the selected unconstrained test functions.

Problem	N	M	D	FEs	MOWCA	MOSOS	MOEA/D	MOSMA
ZDT1	100	2	30	100000	3.9745e-1 (4.57e-3)	3.3274e-1 (1.28e-3)	2.7283e-1 (3.74e-3)	1.3250e-1 (4.96e-3)
ZDT2	100	2	30	100000	3.4926e-1 (3.56e-2)	4.4948e-1 (1.10e-3)	1.4480e-1 (4.32e-3)	1.3701e-1 (2.78e-3)
ZDT3	100	2	30	100000	3.7856e-1 (3.04e-2)	4.7548e-1 (4.33e-2)	6.0592e-1 (4.87e-2)	1.6694e-1 (3.11e-2)
ZDT4	100	2	10	100000	8.8436e-1 (1.12e-1)	4.4169e-1 (2.90e-2)	2.7807e-1 (1.11e-2)	9.7080e-2 (4.00e-3)
ZDT6	100	2	10	100000	4.2211e-1 (5.33e-2)	4.1330e-1 (3.61e-2)	1.4134e-1 (2.16e-3)	1.2754e-1 (5.53e-3)
UF1	100	2	30	100000	8.5200e-1 (2.29e-2)	8.7564e-1 (9.62e-2)	1.0154e+0 (1.36e-2)	3.8568e-1 (9.79e-2)
UF2	100	2	30	100000	4.0331e-1 (4.84e-2)	5.5838e-1 (1.12e-2)	6.6444e-1 (6.80e-2)	2.3911e-1 (7.40e-3)
UF3	100	2	30	100000	3.7250e-1 (2.75e-2)	1.1412e+0 (2.04e-1)	9.9457e-1 (7.76e-3)	1.1007e+0 (2.10e-2)
UF4	100	2	30	100000	3.4252e-1 (2.35e-2)	4.5371e-1 (6.30e-2)	5.5955e-1 (4.29e-2)	1.8376e-1 (1.44e-3)
UF5	100	2	30	100000	9.9502e-1 (8.74e-3)	1.1885e+0 (2.01e-1)	1.0001e+0 (1.34e-4)	8.7244e-1 (6.18e-3)
UF6	100	2	30	100000	1.0162e+0 (1.22e-2)	1.2426e+0 (2.42e-1)	1.0000e+0 (3.88e-7)	8.0721e-1 (5.06e-2)
UF7	100	2	30	100000	4.9296e-1 (6.02e-3)	8.3903e-1 (2.23e-1)	1.0046e+0 (6.51e-3)	1.8959e-1 (3.15e-2)
UF8	100	3	30	100000	5.9951e-1 (2.06e-2)	5.9378e-1 (1.08e-2)	5.8554e-1 (1.82e-1)	1.6357e-1 (4.05e-3)
UF9	100	3	30	100000	6.2083e-1 (2.17e-2)	6.1360e-1 (7.51e-2)	8.2358e-1 (5.84e-2)	2.9605e-1 (2.01e-2)
UF10	100	3	30	100000	6.1987e-1 (2.65e-2)	6.7163e-1 (7.71e-2)	1.0000e+0 (2.77e-6)	2.8938e-1 (1.30e-1)

TABLE 4. Results of the multi-objective algorithms (using SPACING) on the selected unconstrained test functions.

Problem	N	M	D	FEs	MOWCA	MOSOS	MOEA/D	MOSMA
ZDT1	100	2	30	100000	6.6033e-3 (5.41e-4)	6.3174e-3 (3.06e-4)	2.6868e-3 (2.84e-4)	3.1446e-3 (2.82e-4)
ZDT2	100	2	30	100000	6.5610e-3 (5.13e-4)	7.1819e-3 (1.92e-4)	3.8111e-3 (1.35e-3)	3.0210e-3 (1.00e-4)
ZDT3	100	2	30	100000	7.2519e-3 (9.33e-5)	8.3539e-3 (4.41e-4)	3.7316e-3 (3.67e-4)	4.1650e-3 (6.29e-4)
ZDT4	100	2	10	100000	2.9875e-2 (2.75e-3)	7.4689e-3 (2.41e-4)	8.1050e-1 (1.90e-1)	2.5587e-3 (2.49e-5)
ZDT6	100	2	10	100000	6.1549e-3 (2.92e-4)	6.0501e-3 (3.45e-4)	9.4197e-2 (1.29e-1)	2.3385e-3 (3.67e-5)
UF1	100	2	30	100000	1.7612e-2 (6.66e-3)	1.0518e-3 (1.17e-4)	1.3582e-2 (1.34e-2)	4.6609e-4 (1.32e-4)
UF2	100	2	30	100000	5.6148e-3 (1.89e-3)	8.9811e-3 (4.21e-3)	5.0599e-3 (1.06e-3)	4.0469e-3 (8.04e-4)
UF3	100	2	30	100000	7.0326e-3 (5.17e-4)	2.2867e-2 (3.22e-2)	8.7684e-3 (2.99e-3)	4.3421e-3 (6.12e-3)
UF4	100	2	30	100000	5.4915e-3 (7.82e-4)	6.7493e-3 (6.12e-4)	3.7108e-3 (2.21e-4)	3.5166e-3 (9.52e-6)
UF5	100	2	30	100000	6.4018e-3 (3.30e-3)	4.2152e-2 (2.92e-2)	7.4955e-2 (2.34e-2)	1.6083e-5 (2.27e-5)
UF6	100	2	30	100000	2.8014e-3 (2.61e-3)	5.2434e-2 (3.96e-2)	1.7419e-2 (2.37e-3)	4.3918e-8 (6.21e-8)
UF7	100	2	30	100000	8.0963e-3 (5.25e-3)	2.8185e-3 (2.90e-3)	3.9495e-3 (1.24e-3)	2.6846e-3 (3.79e-3)
UF8	100	3	30	100000	2.5775e-1 (1.19e-1)	1.2244e-1 (2.98e-2)	1.4901e-1 (5.49e-3)	6.5931e-2 (7.99e-3)
UF9	100	3	30	100000	3.8672e-1 (5.90e-2)	1.1187e-1 (1.35e-2)	2.3874e-1 (1.45e-2)	7.7053e-2 (4.00e-4)
UF10	100	3	30	100000	1.5654e-1 (4.16e-4)	2.1179e-1 (6.98e-2)	3.0916e-1 (9.03e-2)	1.3305e-5 (7.75e-6)

listed in Table 6 and Table 11. For each problem, the best run-time outcomes are displayed in boldface. The run-time metric is used to calculate each algorithm's quantitative efficiency, considering reduced time complexity. Table 6 and Table 11 show that MOSMA convergence speed ranks first, followed by MOSOS, MOWCA, and MOEA/D. The obtained Pareto front using the MOSMA optimizer is shown in Fig. 7, and Fig. 8 are concerning the true Pareto front for ZDT1-6, and Fig. 9 are concerning the true Pareto front for ZDT7-10.

UF1-10, and the constrained benchmark functions, such as TNK, KITA, CONSTR, OSY, and SRN.

As similar to the previous discussion, the proposed MOSMA and other selected algorithms are applied to 21 real-world engineering design optimization problems, such as 2-bar truss, I-beam, 3-bar truss, 4-bar truss, pressure vessel, helical spring, disk brake, welded-beam, gear-train, speed reducer, tool spindle, CNC machine tool, cantilever beam, car

TABLE 5. Results of the multi-objective algorithms (using IGD) on the selected unconstrained test functions.

Problem	N	M	D	FEs	MOWCA	MOSOS	MOEA/D	MOSMA
ZDT1	100	2	30	100000	5.0230e-3 (1.76e-4)	4.4742e-3 (1.64e-4)	4.0711e-3 (1.27e-4)	3.8898e-3 (4.00e-5)
ZDT2	100	2	30	100000	4.7842e-3 (8.05e-6)	4.9289e-3 (1.08e-4)	3.9485e-3 (5.36e-6)	3.9120e-3 (6.10e-5)
ZDT3	100	2	30	100000	5.2151e-3 (9.64e-5)	5.8920e-3 (1.05e-4)	1.2191e-2 (4.45e-4)	4.9243e-3 (8.56e-5)
ZDT4	100	2	10	100000	2.3998e-1 (8.52e-2)	4.5570e-3 (5.95e-5)	5.6804e-3 (2.25e-3)	3.7941e-3 (1.45e-5)
ZDT6	100	2	10	100000	3.9688e-3 (1.80e-4)	3.5883e-3 (1.44e-5)	3.6873e-3 (5.27e-4)	3.0782e-3 (2.24e-5)
UF1	100	2	30	100000	1.0483e-1 (2.13e-2)	9.9124e-2 (1.27e-2)	2.4081e-1 (8.08e-3)	4.2432e-2 (2.42e-3)
UF2	100	2	30	100000	5.1495e-2 (1.68e-2)	2.9975e-2 (3.56e-3)	1.7568e-1 (3.16e-2)	2.8347e-2 (1.56e-3)
UF3	100	2	30	100000	1.4627e-1 (5.94e-4)	2.6595e-1 (3.65e-2)	2.7174e-1 (8.69e-2)	8.6610e-2 (1.28e-2)
UF4	100	2	30	100000	8.4065e-2 (7.35e-3)	4.5618e-2 (1.84e-3)	7.2472e-2 (4.76e-3)	4.4336e-2 (7.79e-4)
UF5	100	2	30	100000	9.5235e-1 (5.23e-1)	3.7642e-1 (5.34e-2)	4.4809e-1 (2.99e-2)	3.9080e-1 (1.02e-1)
UF6	100	2	30	100000	4.0697e-1 (5.52e-2)	2.5032e-1 (2.22e-1)	3.7607e-1 (3.07e-2)	1.1596e-1 (2.22e-2)
UF7	100	2	30	100000	4.5630e-2 (3.84e-3)	1.9885e-1 (2.11e-1)	5.0500e-1 (1.79e-1)	1.7391e-2 (2.01e-3)
UF8	100	3	30	100000	5.4477e-1 (1.49e-1)	2.5311e-1 (5.03e-2)	2.1728e-1 (1.08e-1)	2.9876e-1 (1.28e-2)
UF9	100	3	30	100000	5.5320e-1 (3.19e-2)	3.5805e-1 (1.97e-2)	2.8886e-1 (4.47e-3)	2.5876e-1 (2.29e-3)
UF10	100	3	30	100000	2.0011e+0 (1.35e-1)	6.1812e-1 (7.49e-2)	7.7617e-1 (1.23e-1)	3.9607e-1 (9.47e-2)

TABLE 6. Results of the multi-objective algorithms (using RUN-TIME) on the selected unconstrained test functions.

Problem	N	M	D	FEs	MOWCA	MOSOS	MOEA/D	MOSMA
ZDT1	100	2	30	100000	7.3996e+0 (5.61e-1)	1.1043e+1 (1.25e-1)	1.0296e+2 (7.00e-3)	6.4451e+0 (2.03e-1)
ZDT2	100	2	30	100000	7.1364e+0 (1.52e-1)	1.0234e+1 (8.44e-2)	1.0209e+2 (4.82e-1)	6.4050e+0 (8.97e-2)
ZDT3	100	2	30	100000	7.1249e+0 (1.30e-1)	8.2029e+0 (1.99e-1)	1.0347e+2 (8.40e-1)	6.3871e+0 (1.26e-1)
ZDT4	100	2	10	100000	6.3961e+0 (5.95e-2)	6.5345e+0 (5.94e-3)	9.8113e+1 (1.92e-1)	5.7882e+0 (5.78e-2)
ZDT6	100	2	10	100000	6.6024e+0 (2.06e-2)	1.5461e+1 (3.69e-1)	1.0148e+2 (1.58e-1)	5.7655e+0 (7.01e-2)
UF1	100	2	30	100000	7.2423e+0 (3.53e-2)	6.9220e+0 (2.19e-1)	1.1198e+2 (5.54e-3)	6.6655e+0 (1.10e-3)
UF2	100	2	30	100000	7.6719e+0 (9.65e-2)	7.3445e+0 (9.56e-3)	1.2559e+2 (2.51e-1)	7.0879e+0 (2.62e-1)
UF3	100	2	30	100000	7.7473e+0 (3.20e-2)	7.5837e+0 (2.11e-1)	1.1254e+2 (3.66e-1)	7.2740e+0 (5.59e-2)
UF4	100	2	30	100000	7.4830e+0 (3.41e-2)	7.8831e+0 (5.84e-2)	1.1204e+2 (3.99e-2)	6.7603e+0 (2.50e-2)
UF5	100	2	30	100000	7.0822e+0 (3.94e-2)	6.5804e+0 (3.83e-2)	1.1176e+2 (3.62e-1)	7.4078e+0 (2.61e-1)
UF6	100	2	30	100000	7.1753e+0 (2.62e-2)	7.0189e+0 (1.58e-1)	1.1175e+2 (5.68e-1)	7.3742e+0 (2.59e-1)
UF7	100	2	30	100000	7.3207e+0 (4.56e-2)	8.0319e+0 (1.47e-1)	1.1166e+2 (4.39e-1)	6.6519e+0 (1.93e-2)
UF8	100	3	30	100000	7.8605e+0 (8.37e-2)	1.0288e+1 (8.07e-1)	1.1664e+2 (1.00e-1)	7.2731e+0 (1.04e-1)
UF9	100	3	30	100000	7.9181e+0 (7.77e-4)	1.0308e+1 (7.79e-1)	1.1635e+2 (3.66e-1)	7.4040e+0 (2.71e-1)
UF10	100	3	30	100000	7.9672e+0 (6.00e-2)	7.9995e+0 (3.24e-1)	1.1624e+2 (2.27e-1)	7.4225e+0 (5.74e-3)

TABLE 7. Results of the multi-objective algorithms (using GD) on the selected constrained benchmark functions.

Problem	M	D	MOWCA	MOSOS	MOEA/D	MOSMA
CONSTR	2	2	3.2591e-4 (1.16e-5)	8.9109e-4 (1.12e-4)	2.9091e-4 (1.10e-5)	1.1898e-4 (8.08e-6)
TNK	2	2	NaN (NaN)	5.1706e-3 (1.41e-4)	3.8768e-4 (7.97e-5)	2.3780e-4 (2.93e-5)
SRN	2	2	2.3699e+0 (1.05e+0)	2.4729e+0 (9.06e-1)	3.5219e-2 (8.63e-3)	3.9666e-2 (1.04e-2)
OSY	2	6	NaN (NaN)	2.0741e-1 (4.85e-1)	7.9047e-1 (1.06e-1)	7.4260e-2 (7.67e-2)
KITA	2	2	1.3891e-3 (2.18e-4)	1.3444e-3 (1.26e-5)	1.1501e-3 (3.72e-7)	6.7687e-4 (2.69e-5)

TABLE 8. Results of the multi-objective algorithms (using IGD) on the selected constrained benchmark functions.

Problem	M	D	MOWCA	MOSOS	MOEA/D	MOSMA
CONSTR	2	2	2.4239e+0 (7.05e-3)	2.8962e-2 (1.78e-5)	5.1573e-2 (4.13e-3)	2.1763e-2 (1.62e-4)
TNK	2	2	NaN (NaN)	5.3874e-3 (1.09e-4)	3.6941e-2 (1.00e-3)	5.4946e-3 (3.48e-4)
SRN	2	2	8.6545e+1 (4.16e+1)	1.0267e+0 (2.23e-2)	1.0042e+1 (1.60e+0)	8.4934e-1 (1.17e-2)
OSY	2	6	NaN (NaN)	2.5710e-1 (1.63e-1)	5.8349e+1 (8.76e+0)	2.8411e+1 (1.57e+0)
KITA	2	2	1.5436e-1 (2.88e-3)	1.2441e-1 (1.24e-2)	9.5856e-2 (1.10e-3)	3.7949e-2 (2.86e-3)

crash, car side-impact, metal cutting tool, multiple disk clutch break, rolling-element bearing, satellite heat pipe, BLDC motor, and isolated safety transformer.

In order to evaluate the convergence output of MOSMA, MOWCA, MOSOS, and MOEA/D about GD metrics, the simulation is carried out for 30 individual runs of all algorithms on all selected real-world engineering design

constrained optimization problems, and the optimal GD values are listed for all selected problems in Table 12. The bold letter indicates the best outcome for each problem. In Table 12, with more than 66.66 % of benchmark functions, the GD (including both mean and SD) value of MOSMA is higher than other algorithms. To compare the diversity success of all algorithms concerning Spacing and Spread

TABLE 9. Results of multi-objective algorithms (using SPACING) on the selected constrained benchmark functions.

Problem	M	D	MOWCA	MOSOS	MOEA/D	MOSMA
CONSTR	2	2	4.3773e-2 (1.79e-4)	4.8466e-2 (3.00e-3)	7.0009e-2 (5.43e-4)	1.6387e-2 (2.35e-4)
TNK	2	2	NaN (NaN)	6.6992e-3 (3.89e-4)	3.9180e-2 (1.79e-2)	4.7473e-3 (4.61e-4)
SRN	2	2	5.5793e+1 (0.00e+0)	1.6470e+0 (1.24e-1)	9.1999e+0 (2.49e+0)	6.7313e-1 (7.85e-2)
OSY	2	6	NaN (NaN)	1.3342e+0 (7.18e-1)	3.6409e+1 (4.28e-1)	2.9570e+0 (9.69e-1)
KITA	2	2	2.0851e-1 (1.94e-2)	1.9471e-1 (2.40e-2)	1.2398e-1 (1.69e-3)	4.4449e-2 (5.17e-3)

TABLE 10. Results of multi-objective algorithms (using SPREAD) on the selected constrained benchmark functions.

Problem	M	D	MOWCA	MOSOS	MOEA/D	MOSMA
CONSTR	2	2	9.8042e-1 (7.68e-3)	9.0790e-1 (7.06e-2)	6.5204e-1 (3.68e-3)	5.5468e-1 (2.49e-2)
TNK	2	2	NaN (NaN)	7.0373e-1 (1.21e-1)	5.6547e-1 (1.02e-1)	3.6133e-1 (4.60e-2)
SRN	2	2	1.2307e+0 (0.00e+0)	3.9230e-1 (1.29e-2)	5.4803e-1 (2.01e-2)	1.5201e-1 (1.49e-2)
OSY	2	6	NaN (NaN)	7.9908e-1 (2.33e-2)	1.1393e+0 (1.14e-1)	7.1835e-1 (1.09e-1)
KITA	2	2	4.9916e-1 (2.09e-2)	6.3628e-1 (9.51e-2)	4.3132e-1 (1.97e-2)	3.0704e-1 (8.20e-3)

TABLE 11. Results of multi-objective algorithms (using RUN-TIME) on the selected constrained benchmark functions.

Problem	M	D	MOWCA	MOSOS	MOEA/D	MOSMA
CONSTR	2	2	9.7004e-1 (3.13e-2)	7.2160e-1 (1.03e-1)	1.9045e+1 (4.05e-2)	6.0797e-1 (7.46e-2)
TNK	2	2	7.1118e-1 (1.26e-1)	6.8539e-1 (5.78e-2)	1.1364e+0 (2.96e-1)	6.2697e-1 (1.19e-2)
SRN	2	2	1.1762e+0 (2.42e-2)	6.3965e-1 (5.65e-3)	1.0239e+0 (2.46e-1)	6.2826e-1 (8.97e-2)
OSY	2	6	6.7079e-1 (3.74e-3)	6.5131e-1 (2.65e-3)	8.9023e-1 (1.89e-3)	6.5641e-1 (6.51e-3)
KITA	2	2	1.5538e+0 (1.90e-2)	6.4419e-1 (5.44e-3)	1.9708e+1 (2.53e-1)	5.5940e-1 (1.16e-2)

TABLE 12. Results of the multi-objective algorithms (using GD) on the selected engineering design optimization problems.

Problem	M	D	MOWCA	MOSOS	MOEA/D	MOSMA
2-bar truss	2	3	NaN (NaN)	3.3323e-2 (9.59e-1)	3.5380e-2 (4.78e-1)	3.2059e-3 (6.30e-2)
3-bar truss	2	2	1.8401e-1 (4.85e-2)	7.0519e-2 (1.48e-2)	9.7862e-2 (3.26e-3)	3.0046e-2 (2.98e-2)
4-bar truss	2	4	1.7518e-2 (2.09e-3)	1.8080e-2 (1.03e-3)	1.8325e-2 (2.95e-4)	8.6231e-3 (5.27e-4)
Gear train continues	2	4	4.2244e-3 (4.42e-3)	4.9797e-3 (4.16e-3)	1.4774e-1 (2.01e-1)	1.0799e-1 (1.51e-1)
Pressure vessel	2	4	NaN (NaN)	1.9465e-2 (2.30e-2)	1.9839e-2 (7.04e-1)	1.8707e-3 (1.26e-2)
Helical spring	2	3	NaN (NaN)	1.6518e-1 (2.01e-1)	1.0486e-1 (1.19e-1)	5.2544e-2 (2.81e-1)
Welded beam	2	4	NaN (NaN)	1.3619e-2 (3.21e-3)	1.2633e-3 (8.33e-5)	1.4868e-2 (7.52e-4)
Disk break	2	4	NaN (NaN)	1.9960e-1 (2.78e-1)	1.1817e-3 (1.29e-4)	9.7573e-4 (2.18e-4)
Speed reducer	2	7	NaN (NaN)	8.7950e-1 (9.83e-3)	1.1938e+0 (1.14e+0)	2.4403e-2 (6.26e-2)
CNC machine tool	2	3	NaN (NaN)	2.9554e-3 (5.59e-4)	8.4012e-4 (5.01e-4)	5.7586e-4 (6.35e-5)
Tool spindle	2	4	3.3456e-1 (9.96e-1)	8.0571e-1 (2.75e-1)	4.0519e-1 (4.62e-1)	3.6258e-2 (4.96e-1)
I-beam	2	4	4.6108e-2 (1.35e-3)	3.0865e-2 (2.77e-3)	2.6579e-2 (1.57e-3)	2.5868e-2 (2.90e-3)
Cantilever beam	2	2	1.6999e-4 (2.53e-6)	2.9175e-5 (2.08e-6)	8.9222e-5 (1.40e-6)	9.3549e-5 (5.00e-6)
Multiple disk clutch brake	2	5	7.1320e-16 (0.0e+0)	3.2259e-3 (6.51e-4)	1.8308e-4 (7.45e-5)	3.7185e-4 (3.89e-5)
Car crash	3	5	4.7609e-2 (2.02e-3)	1.3663e-2 (8.02e-4)	1.1774e-2 (3.93e-3)	1.1583e-2 (3.68e-4)
Car side impact	3	7	1.4822e-2 (6.10e-4)	1.0529e-2 (5.39e-4)	1.1673e-2 (1.62e-3)	7.5748e-3 (2.48e-4)
Metal cutting tools	3	3	3.7644e-4 (4.30e-5)	5.1346e-4 (3.79e-5)	2.8105e-4 (6.60e-5)	4.2866e-4 (8.82e-5)
Rolling element bearing	2	10	NaN (NaN)	7.6563e+3 (6.77e+3)	1.6349e+4 (2.10e+3)	1.9544e-1 (9.43e-3)
Satellite heat pipe	2	5	6.0230e-2 (5.96e-3)	3.3275e-2 (1.10e-4)	5.8838e-2 (1.99e-3)	5.3992e-2 (2.11e-4)
BLDC motor	2	5	NaN (NaN)	3.8237e-4 (6.39e-5)	2.2000e-4 (1.14e-5)	2.0761e-4 (6.69e-6)
Isolated safety transformer	2	7	NaN (NaN)	1.1027e-3 (2.82e-4)	1.5591e-2 (2.10e-2)	9.5552e-4 (5.64e-5)

metrics, the study runs 30 times individually on all selected real-world engineering design constrained optimization problems and then finds the optimal values of Spacing, Spread. The values are listed in Table 13 and Table 14. The value of spacing/spread for the proposed MOSMA is better than other algorithms for more than 69.04 % of all test problems. The robust output of the MOSMA for balancing convergence and diversity is demonstrated by finding the optimal values of the IGD indicator.

By running 30 times on selected engineering design optimization problems independently, the IGD metric of

all algorithms is listed in Table 15. Table 15 shows that the proposed MOSMA ranks first, followed by MOEA/D, MOSOS, and MOWCA. To compare the time complexity of all algorithms for run-time metrics, the run time of all algorithms is listed in Table 16. The results in Table 16 shows that MOSMA convergence speed ranks first, followed by MOSOS, MOWCA, and MOEA/D. The obtained Pareto front using the MOSMA optimizer is shown in Fig. 9 concerning the true Pareto front for all engineering design problems.

Inspecting the results in Table 2 – Table 16 and the optimal Pareto fronts obtained in Fig. 7 – Fig. 9, it is evident

TABLE 13. Results of multi-objective algorithms (using SPACING) on the selected engineering design optimization problems.

Problem	M	D	MOWCA	MOSOS	MOEA/D	MOSMA
2-bar truss	2	3	NaN (NaN)	5.6314e+2 (4.96e+1)	1.0362e+3 (2.50e+2)	5.3497e-2 (1.67e-1)
3-bar truss	2	2	1.4458e+1 (3.09e+0)	1.1279e+1 (7.31e-1)	NaN (NaN)	8.6652e+0 (7.39e-1)
4-bar truss	2	4	2.5331e+0 (1.10e-1)	2.5981e+0 (2.23e-1)	6.6241e-1 (8.95e-4)	2.4435e+0 (4.37e-2)
Gear train continues	2	4	1.2608e-1 (8.45e-3)	7.7423e-1 (9.19e-1)	2.0588e-1 (1.06e-1)	1.0873e+0 (1.35e+0)
Pressure vessel	2	4	NaN (NaN)	2.4354e+5 (2.79e+3)	3.0925e+5 (6.43e+4)	1.4955e-1 (4.37e-3)
Helical spring	2	3	NaN (NaN)	6.6984e+2 (1.29e+2)	2.1515e+3 (3.27e+1)	1.3150e+3 (1.68e+2)
Welded beam	2	4	NaN (NaN)	2.1206e-1 (1.75e-2)	NaN (NaN)	1.7504e-1 (3.67e-2)
Disk break	2	4	NaN (NaN)	8.4921e-2 (6.11e-3)	9.1869e-1 (1.20e+0)	7.6673e-2 (2.86e-4)
Speed reducer	2	7	NaN (NaN)	2.2968e+1 (3.89e+0)	1.1661e+2 (3.42e+1)	1.7183e-1 (7.40e+0)
CNC machine tool	2	3	NaN (NaN)	1.0020e-1 (5.29e-2)	2.0963e-1 (2.52e-2)	2.7147e-2 (5.78e-4)
Tool spindle	2	4	0.0000e+0 (0.00e+0)	6.0450e-3 (3.88e-2)	3.6905e-4 (3.10e-4)	4.6720e-3 (9.19e-1)
I-beam	2	4	5.9204e+0 (4.12e-1)	4.1204e+0 (4.36e-2)	3.0342e+1 (1.11e+1)	3.7523e-1 (9.55e-1)
Cantilever beam	2	2	2.1082e-2 (2.76e-3)	1.8812e-2 (1.38e-3)	5.7855e-2 (2.69e-2)	1.5684e-2 (5.25e-4)
Multiple disk clutch brake	2	5	0.0000e+0 (0.00e+0)	4.5865e-2 (5.02e-4)	4.8525e-2 (1.23e-2)	4.7535e-2 (1.21e-4)
Car crash	3	5	2.2391e-1 (5.17e-2)	2.2740e-1 (2.14e-2)	2.9360e-1 (9.00e-2)	1.8536e-1 (2.35e-2)
Car side impact	3	7	4.3241e-1 (7.26e-2)	2.1379e-1 (8.19e-3)	1.9393e-1 (3.07e-2)	1.1403e-1 (3.61e-3)
Metal cutting tools	3	3	2.5127e-2 (4.35e-4)	2.3003e-2 (2.24e-3)	1.5102e-1 (5.95e-3)	1.7021e-2 (2.64e-6)
Rolling element bearing	2	10	NaN (NaN)	1.3662e+1 (6.84e+0)	5.4522e+3 (0.00e+0)	4.9352e+3 (1.45e+3)
Satellite heat pipe	2	5	9.9518e+0 (2.50e-1)	9.9008e+0 (5.94e-1)	2.6746e-1 (1.69e-3)	9.2570e+0 (1.64e-1)
BLDC motor	2	5	NaN (NaN)	1.9306e-2 (1.58e-3)	4.1656e-2 (3.74e-3)	1.2685e-2 (1.23e-3)
Isolated safety transformer	2	7	NaN (NaN)	4.5027e-1 (4.45e-1)	2.3096e-1 (2.17e-3)	9.2953e-2 (5.98e-2)

TABLE 14. Results of multi-objective algorithms (using SPREAD) on the selected engineering design optimization problems.

Problem	M	D	MOWCA	MOSOS	MOEA/D	MOSMA
2-bar truss	2	3	NaN (NaN)	8.3285e-1 (3.52e-3)	1.0798e+0 (1.94e-1)	6.1586e-1 (1.71e-2)
3-bar truss	2	2	6.1883e-1 (2.56e-2)	8.4752e-1 (4.05e-3)	NaN (NaN)	5.6165e-1 (3.99e-2)
4-bar truss	2	4	5.1085e-1 (3.14e-2)	5.4429e-1 (4.73e-2)	6.2192e-1 (5.40e-3)	4.1710e-1 (1.54e-2)
Gear train continues	2	4	7.0458e-1 (3.14e-2)	1.0302e+0 (3.19e-1)	1.0343e+0 (1.81e-2)	9.5399e-1 (4.19e-1)
Pressure vessel	2	4	NaN (NaN)	5.4976e-1 (2.60e-2)	8.2592e-1 (2.39e-2)	2.3942e-1 (8.74e-3)
Helical spring	2	3	NaN (NaN)	1.5754e+0 (1.30e-1)	7.6712e-1 (1.21e-1)	7.5119e-1 (2.09e-1)
Welded beam	2	4	NaN (NaN)	7.5816e-1 (5.64e-2)	NaN (NaN)	5.4629e-1 (1.04e-1)
Disk break	2	4	NaN (NaN)	6.7509e-1 (6.37e-2)	1.0576e+0 (6.04e-1)	5.2227e-1 (1.60e-3)
Speed reducer	2	7	NaN (NaN)	8.3379e-1 (4.73e-4)	1.3657e+0 (1.19e-1)	6.9187e-1 (1.19e-2)
CNC machine tool	2	3	NaN (NaN)	9.6555e-1 (9.76e-2)	1.1709e+0 (5.60e-2)	1.0636e+0 (1.59e-1)
Tool spindle	2	4	1.0000e+0 (0.00e+0)	6.7538e-1 (2.19e-2)	1.0380e+0 (4.93e-2)	3.7136e-1 (3.97e-3)
I-beam	2	4	5.6545e-1 (1.73e-2)	7.5217e-1 (2.67e-2)	1.0762e+0 (2.00e-2)	4.4907e-1 (2.94e-2)
Cantilever beam	2	2	6.2294e-1 (9.06e-3)	8.6279e-1 (1.24e-1)	1.4518e+0 (1.81e-2)	4.8883e-1 (4.49e-2)
Multiple disk clutch brake	2	5	1.0000e+0 (0.00e+0)	1.3878e+0 (5.77e-2)	6.2063e-1 (7.82e-3)	5.7265e-1 (5.58e-2)
Car crash	3	5	5.1697e-1 (2.63e-2)	6.7946e-1 (4.08e-2)	7.3413e-1 (5.05e-2)	4.6747e-1 (1.31e-1)
Car side impact	3	7	7.4408e-1 (8.90e-2)	5.0136e-1 (4.72e-2)	4.3655e-1 (2.20e-2)	3.7426e-1 (1.01e-2)
Metal cutting tools	3	3	4.4303e-1 (4.41e-2)	4.8807e-1 (4.39e-2)	1.0956e+0 (9.47e-4)	2.2487e-1 (2.73e-2)
Rolling element bearing	2	10	NaN (NaN)	1.0637e+0 (3.62e-2)	1.0626e+0 (0.00e+0)	1.1180e+0 (9.51e-2)
Satellite heat pipe	2	5	6.9109e-1 (1.62e-2)	7.0590e-1 (1.11e-1)	7.5193e-1 (3.80e-2)	5.3056e-1 (1.11e-2)
BLDC motor	2	5	NaN (NaN)	9.2617e-1 (8.90e-3)	9.6090e-1 (1.36e-2)	8.5440e-1 (2.44e-3)
Isolated safety transformer	2	7	NaN (NaN)	8.3822e-1 (2.21e-2)	9.4306e-1 (1.06e-1)	9.1019e-1 (1.18e-1)

that the proposed MOSMA can provide a relatively accurate estimation of the true Pareto optimal solutions for all constrained, unconstrained, and engineering design optimization problems. The high coverage can be seen in Figs. 7-9. Note that NaN in all tables stands for Not a Number, which refers to the algorithms that the results are not available for the respective problem.

D. BRIEF DISCUSSIONS

In summary, findings and analyses demonstrate that MOSMA has a very high speed of convergence. This comes from the fact that the best solution often leads significantly to the enhancement of other solutions. This section discusses MOSMA optimizer benefits, such as high accuracy

(convergence) and high coverage on most case studies. The former is an indication of high exploitation by MOSMA. Since MOSMA uses the same methodology as SMA, it inherently benefits from high exploitation. However, this is not enough for a posteriori algorithm. The MOSMA optimizer also represents exploration positively due to the SMA's operator and MOSMA's crowding distance. Sudden changes in Eq. 1 results in high exploratory behaviour. The non-dominated sorting mechanism and crowding distance operators also contribute to the exploration of MOSMA. The high coverage of Pareto optimal solutions achieved by MOSMA on many of the benchmark problems would be another finding. This probably originated from the processes of leader selection and archive maintenance.

TABLE 15. Results of the multi-objective algorithms (using IGD) on the selected engineering design optimization problems.

Problem	M	D	MOWCA	MOSOS	MOEA/D	MOSMA
2-bar truss	2	3	NaN (NaN)	2.9788e+2 (1.31e+1)	7.6272e+2 (4.57e+1)	2.4611e-2 (4.42e-3)
3-bar truss	2	2	1.9681e+2 (1.26e+1)	5.0124e+0 (4.10e-1)	4.7261e+2 (2.42e-2)	4.1086e-2 (4.12e-1)
4-bar truss	2	4	1.7570e+0 (8.06e-2)	1.7645e+0 (7.77e-2)	4.9818e-1 (3.48e-3)	1.4684e+0 (1.50e-3)
Gear train continues	2	4	7.1468e-2 (9.06e-3)	7.1763e-2 (2.54e-3)	1.0610e-1 (7.79e-3)	5.9599e-2 (8.53e-3)
Pressure vessel	2	4	NaN (NaN)	2.0306e-4 (1.12e-4)	2.8128e-3 (6.79e-3)	1.6118e-5 (3.91e-2)
Helical spring	2	3	NaN (NaN)	9.5295e-2 (4.29e-1)	2.9251e+3 (1.17e+3)	1.5846e-1 (1.18e-1)
Welded beam	2	4	NaN (NaN)	1.1635e-1 (2.60e-3)	1.0831e+1 (6.15e-1)	9.2482e-2 (6.76e-4)
Disk break	2	4	NaN (NaN)	6.7926e-2 (9.55e-3)	9.0921e-2 (1.26e-2)	4.5821e-2 (2.98e-4)
Speed reducer	2	7	NaN (NaN)	8.2716e+1 (9.73e+1)	9.8328e+1 (9.58e-1)	1.1985e-1 (2.04e-2)
CNC machine tool	2	3	NaN (NaN)	1.9219e-1 (1.88e-1)	1.2926e-1 (2.13e-2)	4.7609e-2 (2.35e-2)
Tool spindle	2	4	6.6314e-2 (3.35e-4)	4.0499e-2 (1.39e-2)	2.9660e-2 (5.65e-3)	3.1374e-3 (1.86e-1)
I-beam	2	4	5.5490e-1 (5.43e-2)	7.5335e+0 (7.09e+0)	1.4232e-1 (1.57e-1)	1.8313e-2 (1.09e-2)
Cantilever beam	2	2	1.6809e-2 (1.54e-3)	9.0251e-3 (1.09e-3)	4.5101e-2 (2.76e-2)	6.8705e-3 (3.84e-5)
Multiple disk clutch brake	2	5	6.7811e-1 (0.00e+0)	6.5230e-3 (1.52e-5)	2.8682e-2 (4.53e-3)	2.8565e-3 (2.26e-5)
Car crash	3	5	7.3726e-1 (4.03e-1)	1.2131e+0 (9.99e-1)	1.7669e+0 (1.14e-2)	3.1731e-1 (1.28e-1)
Car side impact	3	7	8.0912e-1 (4.67e-2)	2.5525e-1 (1.20e-2)	1.6045e-1 (5.28e-3)	2.4546e-1 (6.63e-3)
Metal cutting tools	3	3	1.6564e-2 (9.54e-4)	2.1968e-2 (6.83e-3)	1.8009e-1 (2.39e-5)	1.3620e-2 (1.13e-4)
Rolling element bearing	2	10	NaN (NaN)	1.2554e-3 (3.78e-1)	4.6399e-2 (8.59e-2)	2.4967e-2 (3.99e-3)
Satellite heat pipe	2	5	5.2999e+0 (3.17e-1)	5.2066e+0 (3.78e-1)	1.0023e+1 (5.91e+0)	4.2736e+0 (1.12e-2)
BLDC motor	2	5	NaN (NaN)	3.1337e-2 (3.64e-3)	3.1474e-1 (2.57e-3)	3.1435e-1 (1.12e-2)
Isolated safety transformer	2	7	NaN (NaN)	6.0325e-1 (4.51e-1)	2.0043e+0 (2.63e+0)	1.6970e-1 (6.46e-3)

TABLE 16. Results of multi-objective algorithms (using RUN-TIME) on the selected engineering design optimization problems.

Problem	M	D	MOWCA	MOSOS	MOEA/D	MOSMA
2-bar truss	2	3	9.0140e-1 (1.27e-2)	6.4696e-1 (3.75e-3)	1.4945e+1 (8.76e-2)	5.6025e-1 (9.89e-3)
3-bar truss	2	2	1.1119e+0 (5.06e-2)	6.4244e-1 (3.64e-3)	1.0242e+1 (6.80e-2)	5.5248e-1 (5.77e-3)
4-bar truss	2	4	1.1303e+0 (1.12e-2)	6.4722e-1 (7.47e-3)	1.9182e+1 (2.07e-2)	5.5629e-1 (1.25e-3)
Gear train continues	2	4	9.6741e-1 (3.75e-3)	6.4441e-1 (4.81e-3)	1.9032e+1 (2.04e-1)	5.7630e-1 (8.35e-3)
Pressure vessel	2	4	8.3633e-1 (4.79e-3)	6.5245e-1 (9.63e-4)	2.0083e+1 (7.79e-2)	5.6579e-1 (2.01e-3)
Helical spring	2	3	6.1667e-1 (1.16e-2)	6.5142e-1 (4.91e-3)	1.6444e+1 (1.60e-1)	7.0801e-1 (5.38e-3)
Welded beam	2	4	7.0200e-1 (5.87e-3)	6.5404e-1 (1.91e-3)	1.7988e+1 (1.86e-2)	5.7651e-1 (5.21e-3)
Disk break	2	4	8.0508e-1 (4.32e-3)	6.6086e-1 (9.83e-5)	1.9519e+1 (3.96e-1)	5.8525e-1 (6.80e-3)
Speed reducer	2	7	7.3675e-1 (3.18e-2)	6.7976e-1 (7.25e-3)	1.9829e+1 (9.74e-2)	7.0924e-1 (2.41e-2)
CNC machine tool	2	3	6.2314e-1 (1.02e-2)	6.6234e-1 (3.83e-3)	1.8570e+1 (5.98e-3)	6.0503e-1 (1.86e-3)
Tool spindle	2	4	1.0218e+0 (9.13e-3)	6.7015e-1 (2.84e-3)	1.2695e+1 (5.76e-3)	6.0432e-1 (6.45e-3)
I-beam	2	4	1.2065e+0 (8.39e-2)	6.5322e-1 (1.74e-3)	1.8650e+1 (1.56e-1)	5.7401e-1 (3.92e-3)
Cantilever beam	2	2	1.4981e+0 (1.39e-2)	6.5634e-1 (5.25e-3)	1.8497e+1 (6.49e-2)	5.7275e-1 (8.61e-3)
Multiple disk clutch brake	2	5	9.1096e-1 (3.18e-2)	6.6418e-1 (1.66e-3)	2.0413e+1 (1.92e-1)	5.9028e-1 (2.78e-4)
Car crash	3	5	1.2549e+0 (3.80e-2)	7.0231e-1 (4.23e-3)	1.4819e+1 (8.23e-2)	6.2795e-1 (4.27e-3)
Car side impact	3	7	1.7124e+0 (1.61e-2)	7.2202e-1 (5.94e-3)	1.5853e+1 (9.25e-2)	6.5690e-1 (4.33e-3)
Metal cutting tools	3	3	2.1953e+0 (3.47e-2)	7.5626e-1 (7.98e-5)	1.0991e+1 (8.31e-2)	6.6335e-1 (8.94e-3)
Rolling element bearing	2	10	3.5236e+1 (2.21e+0)	5.3167e+0 (3.43e-2)	1.9173e+1 (6.37e-2)	1.2646e+2 (7.55e-1)
Satellite heat pipe	2	5	1.0723e+0 (1.21e-2)	6.7581e-1 (6.60e-3)	1.9344e+1 (6.35e-2)	5.9721e-1 (6.95e-3)
BLDC motor	2	5	2.8470e+0 (2.42e-1)	2.5737e+0 (7.93e-3)	3.9219e+1 (4.48e-1)	2.5931e+0 (4.48e-2)
Isolated safety transformer	2	7	2.9997e+0 (9.02e-3)	3.0260e+0 (2.46e-2)	4.4632e+1 (2.87e-1)	3.1593e+0 (1.45e-2)

V. CONCLUSION AND FUTURE DIRECTIONS

This paper introduced a multiple-objective version of the SMA optimizer. Motivated from the main idea of NSGA-II, a non-dominated ranking and crowding distance approach were integrated into conventional SMA to design the MOSMA algorithm. The proposed method was tested on 41 case studies, including unconstrained/constrained/real-world engineering design problems. The result proves that the MOSMA optimizer can estimate Pareto optimal solutions for

all types of discrete/continuous Pareto front problems. All the PF obtained were highly distributed across all objectives. The analysis of the metrics, such as GD / IGD / Spread / Spacing / RUNTIME, showed the superiority and balance between the exploration phase and exploitation phase in MOSMA. As per the obtained results and comparative study on different optimizers, it is concluded that the MOSMA has merits among the recent competitive algorithms. The proposed MOSMA is acceptable for two and three objective problems.

The proposed MOSMA can be directly applied to any engineering design problems due to its local front avoidance and high exploration capability.

The authors are planning to apply the proposed MOSMA and its enhanced variants to practical problems such as developing the solar models, realizing and developing the structural health assessment, modelling wireless sensor networks and deployment cases, and problems and concerns in power engineering. For future works, the method's proposal to handle many objectives optimization using MOSMA is also recommended. Also, the binary and mixed-integer version on MOSMA is worth of investigation.

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