



UNIVERSITI PUTRA MALAYSIA

**A NEURAL NETWORK SOLUTION TO SINGULAR CONFIGURATION IN
TRAJECTORY TRACKING OF A SERIAL ROBOT**

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FK 2009 56



**A NEURAL NETWORK SOLUTION TO SINGULAR CONFIGURATION
IN TRAJECTORY TRACKING OF A SERIAL ROBOT**

**By
ALI T. HASAN**

**Thesis Submitted to the School of Graduate Studies, Universiti Putra Malaysia,
in Fulfilments of the Requirements for the Degree of Doctor of Philosophy**

September 2009



DEDICATION

A Special Dedication To
My Family



Abstract of thesis presented to the Senate of Universiti Putra Malaysia in
fulfilment of the requirements for the degree of Doctor of Philosophy

**A NEURAL NETWORK SOLUTION TO SINGULAR CONFIGURATION IN
TRAJECTORY TRACKING OF A SERIAL ROBOT**

By

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September 2009

Chairman: Associate Professor Napsiah Ismail, PhD

Faculty: Engineering

Singularities and uncertainties in arm configurations are the main problems in kinematics of serial robots. The complexity in the solution arises from robots geometry and non-linear equations (trigonometric equations) occur when transforming between Cartesian and joint spaces where multiple solutions and singularities exist. Mathematical solutions for the problem may not always correspond to the physical solution and methods of solution depend on the robot configuration.

In this research, a trajectory tracking approach is proposed for a 6 Degrees Of Freedom (DOF) serial robot manipulator. The proposed solution is carried out through two stages. First the kinematics model of the Fanuc *M710i* robot was solved using the D-H method to show the exact location of singular



configurations of the robot, and then Artificial Neural Networks (ANNs) are trained to overcome these arising problems. Solving the Inverse Kinematics (IK) of serial manipulators by using ANNs has two problems, one of these is the selection of the appropriate configuration of the network and the other is the generating of suitable training data sets.

In this research, although this is very difficult in practice, training data were recorded experimentally from sensors fixed on each joint to overcome the effect of kinematics uncertainties presence in the real world such as ill-defined linkage parameters, links flexibility and backlashes in gear train. Off-line training was implemented for the experimentally obtained training data.

Two networks configurations from the literature were tested and developed following the recommendations of the original authors, then compared to find the best configuration to be used. First the effect of orientation of the tool was examined (as one of the networks does not considered the effect of orientation while the other network does), and then the effect of the Jacobian matrix to the solution for the both configurations was examined.

Performance comparison shows that when the effect of the orientation of the tool was considered in the solution with the Jacobian matrix effect, better results in terms of precision and iteration during training the ANN were obtained.

The effect of the network architecture was also examined in order to find the best network configuration to solve the problem. A network with all the parameters considered together in one network has been compared to six different networks, where the parameters of every joint were considered independently. Results obtained show that having one network considering all the problem's parameters together give a better response than using 6 different networks representing the parameters of each joint apart from other joints.

The resultant network with the best configuration was tested experimentally using new different set of data that has never been introduced to the network before, this data set was meant to pass through the singular configurations, in order to show the generality and efficiency of the proposed approach.

Experimental trajectory tracking has shown the ability of the proposed Artificial Neural Networks approach to overcome the disadvantages of using some schemes like the Fuzzy Learning Control for example that only remembers the most recent data sets introduced, as the literature has shown.

Abstrak tesis yang dikemukakan kepada Senat Universiti Putra Malaysia
sebagai memenuhi keperluan untuk ijazah Doktor Falsafah

**PENYELESAIAN RANGUAIAN NEURAL UNTUK TATARAJAH SINGULARITI
BAGI PENJEJAKAN TRAJEKTORI ROBOT SERIAL**

Oleh

ALI T. HASAN

September 2009

Pengerusi: Prof. Madya Datin Napsiah Ismail, PhD

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Singulariti dan ketidakpastian dalam konfigurasi lengan adalah masalah utama dalam kinematik robot bersiri. Kerumitan dalam penyelesaian timbul daripada geometri robot dan persamaan taksekata (persamaan trigonometri) terjadi apabila perubahan antara satah Kartesian dan ruang sambungan di mana penyelesaian berbilang dan singulariti wujud. Penyelesaian matematik untuk masalah ini mungkin tidak selalunya selaras dengan penyelesaian fizik dan kaedah-kaedah penyelesaian bergantung pada konfigurasi robot.

Dalam penyelidikan ini, satu pendekatan penjejakan trajektori telah dicadangkan bagi enam darjah kebebasan pergerakan (DOF) pengolah robot bersiri. Penyelesaian yang dicadangkan dijalankan dengan dua peringkat. Pertama model kinematik robot Fanuc *M710i* diperolehi menggunakan kaedah D-H untuk



menunjukkan lokasi sebenar konfigurasi singular robot, dan kemudian Rangkaian Neuro Buatan (ANNs) telah dilatih bagi mengatasi masalah yang muncul.

Menyelesaikan kinematik songsang (IK) pemutar belit bersiri dengan menggunakan ANNs mempunyai dua masalah, satu daripadanya adalah pemilihan konfigurasi rangkaian yang padan dan yang lain ialah penjanaan set-set data latihan yang sesuai.

Dalam penyelidikan ini, data latihan telah direkodkan secara eksperimen daripada pengesan yang ditetapkan pada setiap sendi untuk mengatasi kesan ketidakpastian kinematik yang hadir di dalam dunia sebenar seperti parameter rangkaian yang tidak ditakrif dengan baik, hubungan kelonggaran dan tendangan dalam gear latihan. Latihan luar talian telah dilaksanakan secara eksperimen untuk memperoleh data latihan.

Dua konfigurasi rangkaian daripada pembacaan telah diuji dan dibangunkan mengikut cadangan penyelidik asal, kemudiannya dibandingkan bagi mencari konfigurasi terbaik untuk digunakan. Pertama, kesan orientasi alat telah diperiksa, dan kemudian kesan matriks Jacobian untuk penyelesaian bagi kedua-dua konfigurasi juga telah diperiksa.

Perbandingan prestasi menunjukkan bahawa apabila kesan orientasi alat dipertimbangkan dalam penyelesaian dengan kesan matriks Jacobian,

keputusan lebih baik dari segi ketepatan dan lelaran semasa latihan ANN dialami.

Kesan seni bina rangkaian telah juga diperiksa bagi tujuan mencari konfigurasi rangkaian yang terbaik untuk menyelesaikan masalah. Satu rangkaian dengan semua parameter dianggap bersama dalam satu rangkaian telah dibandingkan dengan enam rangkaian berbeza, di mana parameter bagi setiap sendi dianggap secara bebas. Keputusan yang diperolehi menunjukkan bahawa mempunyai satu rangkaian dengan mempertimbangkan kesemua parameter masalah bersama menunjukkan gerak balas yang lebih baik daripada menggunakan enam rangkaian berbeza yang mewakili parameter bagi setiap sendi yang bersendirian.

Rangkaian yang dihasilkan dengan konfigurasi terbaik telah diuji secara eksperimen dengan menggunakan tiga set data baru berbeza yang tidak pernah diperkenalkan kepada rangkaian sebelum ini, set data ini telah ditetapkan untuk melalui konfigurasi singular, dengan tujuan untuk menunjukkan keluasan makna dan kecekapan bagi pendekatan yang telah dicadangkan.

Eksperimen penjejakan trajektori telah menunjukkan keupayaan pendekatan Rangkaian Neuro Buatan cadangan untuk mengatasi kelemahan dalam menggunakan skema-skema seperti kawalan pengajaran Fuzzy contohnya yang hanya mengingat set data yang paling mutakhir diperkenalkan, seperti yang ditunjukkan dalam pembacaan.

ACKNOWLEDGMENTS

First of all, Great thanks to the Most Gracious and Most Merciful **ALLAH** (S.W.T) for the help of which this work would not have been possible without.

I wish to express my profound appreciation and sincere gratitude to the chairman of the supervisory committee, Associate Professor Datin Dr. Napsiah Ismail for her kind assistance, support, advice, encouragement, and suggestions throughout this work and during the preparation of this thesis.

Furthermore, I would like to take this opportunity to forward my deepest appreciation and gratitude to supervisory committee members Associate Professor Dr. Ishak Aris, Associate Professor Dr. Mohammad Hamiruce Marhaban and Professor Dr. A.M.S. Hamouda, I am grateful for their willingness to serve on my supervisory committee, constant encouragement, helpful advice and fruitful discussions.

Thanks and acknowledgements are meaningless if not extended to my parents who deserve my deepest appreciation. I am grateful for the countless sacrifices they made to ensure that I could pursue my PhD, and for always being there for me. Real and deepest thanks to them (May **ALLAH** (S.W.T) bless and protect them and may live long and healthy). All praise and thanks words said to them will not be enough.



A particular note of thanks is also given to Miss Normalina Jamaluddin, the science officer of the Spatial and Numerical Modeling Lab. (ITMA), and, also to Mr. Muhamad Saufi Mohd Kassim and Mrs. Rosiah Osman the science officers of the Intelligent Systems and Robotics Lab. (ITMA), for their assistance in providing the necessary tools to perform this work.

I would like to express my appreciation and thanks to all who have taught me during my life. Lastly but not least, very very special thanks to my brothers and sister for their love, support and encouragement



I certify that a Thesis Examination Committee has met on the 29th of September 2009 to conduct the final examination of Ali T. Hasan on his thesis entitled " A Neural Network Solution To Singular Configuration In Trajectory Tracking of A Serial Robot " in accordance with the Universities and University Colleges Act 1971 and the Constitution of the Universiti Putra Malaysia [P.U. (A) 106] 15 March 1998. The Committee recommends that the student be awarded the Doctor of Philosophy.

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DECLARATION

I declare that the thesis is my original work except for quotations and citations which have been duly acknowledged. I also declare that it has not been previously, and is not concurrently, submitted for any other degree at Universiti Putra Malaysia or at any other institution.

ALI T. HASAN

Date:

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