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MODELLING AND ANALYSIS ON ROBOTIC MANIPULATORS

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ABSTRACT

Following Guillaume de l'Hôpital's initial proposal of fractional calculus (FC), the first practical use of fractional differential operators in electrical transmission line analysis was made by Oliver Heaviside in 1890. The scientific and technical sectors did not warm up to FC since it did not provide a physical explanation. Derivatives and integrals of fractional order (FO) provide generalisation of the point property, which is a beautiful feature of this domain compared to integer order (IO) ones, which adhere to a point property.A pendulum on a cart system is one example of an unstable and challenging-to-manage robotic system that is the subject of this thesis. Industries that deal with the transportation of heavy loads place a premium on the proper administration of 2-D gantry crane systems; these cranes are often controlled by people, who must depend on their own skills and expertise to move the enormous items, which may result in dangerous accidents. In this thesis, a novel technique is proposed to create the controller using an augmented FO model of the system, rather than the hit-and-miss strategy to generate the fractional model. We compare the results of our approach with those of existing fractional-order models. Our proposed fractional-order model is an improvement over these existing methods that can double the performance.

1. INTRODUCTION

Dynamic systems defined by equations of either integer or fractional order may be studied using the FC, a kind of differential calculus characterised by integrals and derivatives in fractional order. A number of uses for FC have been identified, especially in control systems, and its popularity as a research tool has skyrocketed. Modelling based on fractional system orders yields better results than the integer model. The Integer Order Model may be seen as an approximation of the FO model, according to one perspective.The very challenging use of the fractional model yields improved performance, which includes resilience, transient stability, noise filtering, and disturbance rejection. Another major obstacle is system-specific controller design, but partial order (FO) controllers have shown to be quite effective in this sector as well. In his study, Podlubny first identified FO Differentiators and FO Integrators as FOPID controllers [1,2].There is more room for precise and accurate implementation with FOPID controllers because of the many customisable parameters and the opportunity to customise the controller to specific system demands. Riemann, Liouville, and Weyl were among the renowned mathematicians who helped shape the FC. Over the years, several scholars have contributed to the expanding corpus of literature on fractional calculus[3,5], including Sonin, Krug, Abel, Fourier, Lacroix, Grunwald, Leibniz, and Letnikov [4]. The first monograph on fractional calculus was published in 1974 [5].Recent years have seen the realisation of FO systems' potential to characterise processes, concepts, and systems over a broad frequency and time range using compact and calculable models [6-8].

Modern control systems include FO controls and focus their attention on signal filtering approaches to regulate unwanted and inappropriate plant response characteristics [9, 10].
In the fields of control engineering and robotics, the fractional integrated differential operator (FC operator) is a very attractive operator. The FO Integral Model is shown and its application in control engineering is addressed by using transient and frequency responses.

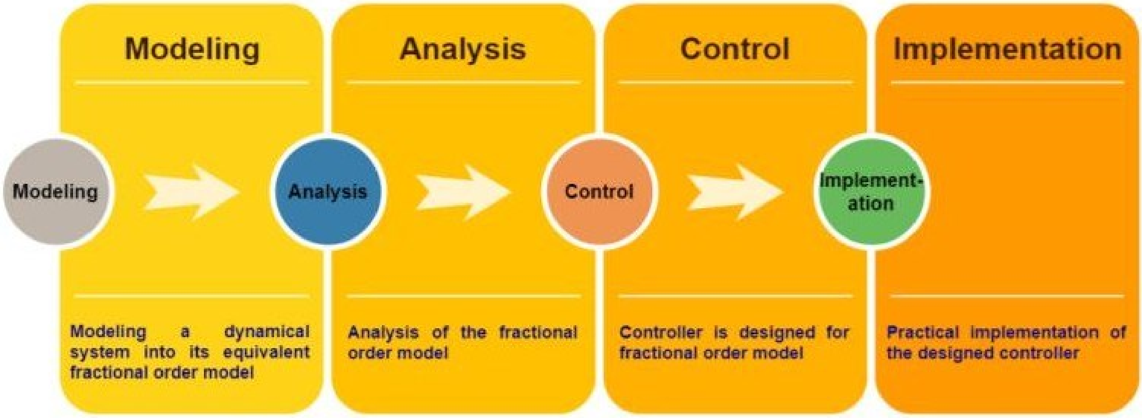

Figure 1: Applications of Fractional Calculus on Dynamical Systems

Oustaloup (1991) develops an FC algorithm for the control of dynamical systems. A general-purpose PID controller called a PIvDŽ, which combines a "m" order and a "l" order integration differentiator, was first suggested by Vinagre et.al. and then used in diverse settings. Furthermore, some FO controller tuning methodologies provide a more flexible tuning strategy. Electric cars, DC motor performance, magnet levitation, and the dynamic behaviours of power systems are some of the latest areas where FO controllers have found use.

2. STUDIES ON ROBOTIC MANIPULATORS

The electrical supply, controls, and manipulators are the main components of an industrial robot. I robotic braces and (ii) a body that moves in tandem with the robot to place components and navigate a work area make up the robotic manipulators. Handler robots are constructed using several joint and The experimental demonstration of the performance of flexible link and flexible joint manipulators is shown in this book, along with connection combinations. The inflexible individual is the link between the axes or joints. The axes are detachable components of the manipulator robot that allow the connecting connections to move relative to one another.Robotic manipulators have significant control issues such vibration and static distinction of external influences. Design flaws may lead to decreased accuracy, longer setup times, and controller design complications.

Robotic manipulators have been a focus of study for a long time. Among the many applications for robot manipulators are the following: coordinating sprays, picking and locating objects, dispersing bombs, evacuating hazardous areas, and even slicing vegetables. In order to do the operation efficiently, the control of these robotic manipulators is crucial.What follows quick overview of robot manipulators for FO modelling and controller design is provided in the next paragraphs.

Supported by Simulations

Oustaloup and colleagues suggested a CRONE control system in 1990, specifically the non-integer derivative applied to robot control, which paved the way for the early 1990s FC control of robot handling devices. Five years later, in 1995, Machado created a method for controlling robotic manipulators' movements using a fractional order PID control. After three years of investigation, Machado et al. determine the manipulators' positions and forces using FC again.In 1998, Machado et al. put up an approach for controlling FO hybrid robot manipulators using an integer model. This strategy was backed by simulation results that used FDI.

Supported by Experiment

Lightweight, flexible manipulation tip position control using FC-based controller design and fractional order PD controller methods were developed by Monje et al. in 2007 for a single flexible manipulator. We present and experimentally validate a fractional controller for an integer model. Barbosa et al. (2010) proposed that FC affects the speed control of the servo system. The servo motor system integrator model and the test results are both supported by the study work's usage of a FO PID controller (with various combinations).Based on their experimental findings, Luo et al. (2011) suggested researching the synthesis of proportional derivative FO control systems. For well-defined Membrane Loading fractional models, FO PD control is used for both control and experimental assistance. The integer manipulation model is equipped with an adaptive FO controller that was designed by Nikdel et al. and has been experimentally validated. A fractional controller based on empirically validated continuous sliding order control was created by Wang et al. [143].

FRACTIONAL MODELING OF ROBOTIC SYSTEMS

Prior to beginning to model any system, it is crucial to have a clear goal in mind. The future of system modelling is dictated by them. The process of developing the fundamental equations of a model begins when the system to be represented has been identified. This is a visual depiction of the system's operational data. Assumptions may help put these pieces of data into words. Nevertheless, this kind of investigation might be used by future system enquiries to support their hypotheses. It is possible to deduce the system's mathematical equations from assumptions that are sufficiently accurate.

In this chapter, we will look at the FO system's Laplace transform definition from [154] using fractional embedding of robotic systems. Below you can see the Laplace transform of the system.

This chapter looked at a number of systems. This chapter is based on the model equations from Chapter 2. It is possible to derive the FO model by using the FO Laplace transformation principle with all initial conditions set to 0.

2.1 Fractional Modeling

The performance of a fractional system is superior to that of its integer counterpart. Despite its complexity, the fractional model improves performance in areas like storm refusal, noise filtering, transient strength, resilience, and more. Finding the best possible controller to implement in a given system is another critical area; fractional controllers have shown great promise in this area. The concept of a fractional order PID controller (FOPID) was first introduced in Podlubny's research, which combined a FO-system integrator with a FO-differentiator.

$$L[Dx(t) - 3D^{\frac{1}{2}}x(t) + 2D^{0}x(t) = 0]$$

$$sX(s) - x(0) - 3s^{\frac{1}{2}}X(s) + 3D^{-\frac{1}{2}}x(0) + 2x(s) = 0$$

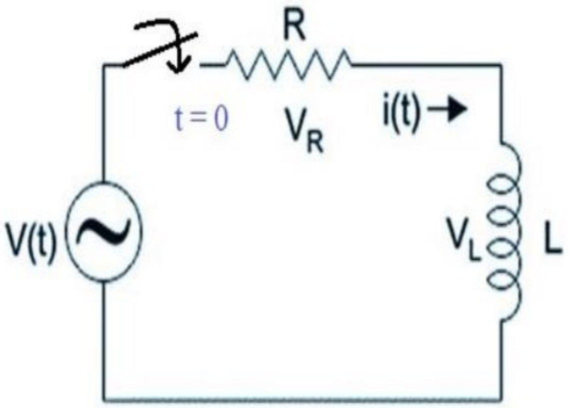

Figure 3.1: RL Circuit

Understanding fractional modelling is made easier by using a basic RL circuit as an example. In Figure 3.1, we can see the RL circuit in action, which consists of a series connection between a resistor (R) and an inductor (L) and a switch that goes to the power source. Because the inductor prevents a rapid change in current, the initial conditions of this circuit are all zero (i(0)=0) when the switch closes at time t=0.

Fractional Embedding to Missile Launching Pad/Vehicle (MLV)

Now, if we consider multi-input and multi- output systems, let us move to a bit greater complexity.

$$H(s) = \begin{pmatrix} \frac{0.1s^2+0.24}{s^4+1.64s^2} & \frac{-0.03}{s^2+1.64} \\ \frac{-0.01}{s^2+1.64} & \frac{-0.004}{s^2+1.64} \end{pmatrix}$$

A missile launch vehicle consists of a ground-to-ground missile or missiles, control (human and mechanical), and the means to control and operate the launch of such weapons. One uses the missiles to fire off a missile. A lot of rocket ships use hand controls. It is necessary to regulate the launch vehicles' angular motions for accurate missile launch.

3. EXPERIMENTAL VALIDATION

How well a FO controller serves real-time systems is shown in this chapter. Here we take a look at three distinct controller design situations. First, there's the IO model and FO controller architecture for the system. The IO Controller and FO model comprise the second strategy. Finally, we have the FO model and controller. Experiments on two separate robotic manipulators support the controller concept in all three of these scenarios.

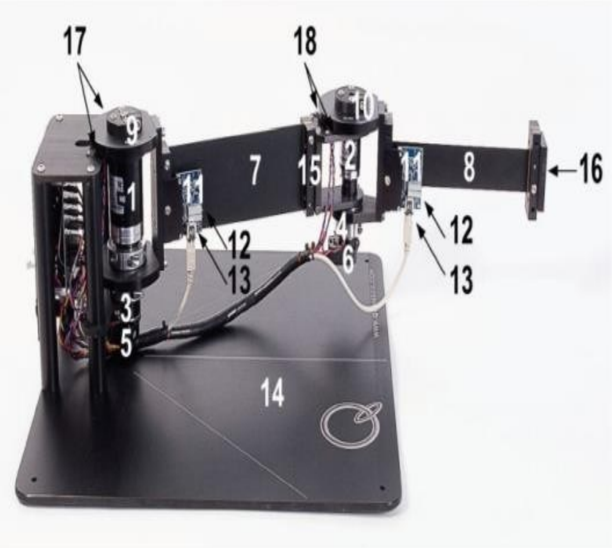

Figure 4.1 shows a 2DOF serial flexible link robotic manipulator and Figure 4.2 shows a 2DOF serial flexible joint robotic manipulator, both of which were considered while designing the FO controller.

Figure 4.1: 2DOF Serial Link Robotic Manipulator.

Figure 4.2 shows the 2DOF Serial Flexible Joint (2DSFJ) Robot. Two symphony gearboxes driven by DC motors and a two-bar sequential linkage make up this robot setup. Both joints do not budge. The two springs used by each adjustable joint are replaceable. You may adjust the positioning of each spring end to different anchor locations along the support bars using the thumbscrew tool. Come with me as I break down the many parts of these robots.

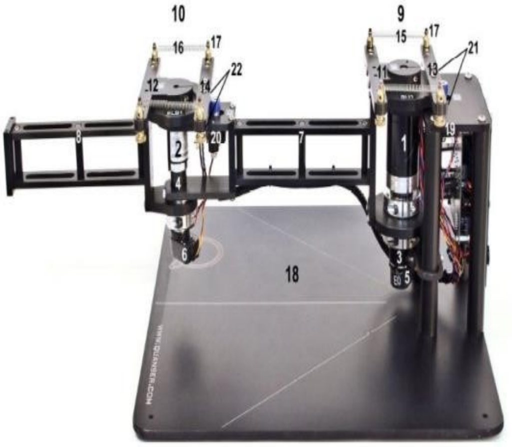

Figure 4.2: 2DOF Serial Joint Robotic Manipulator

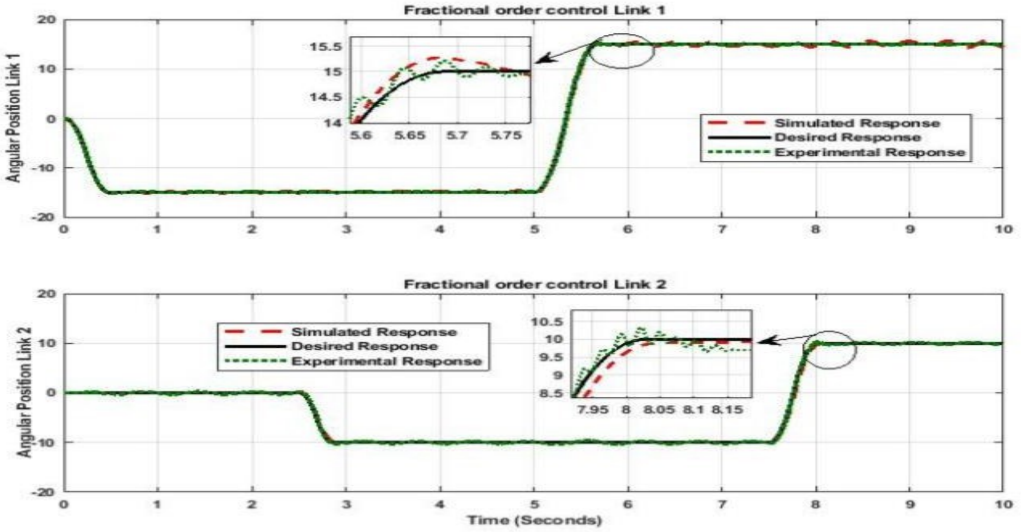

Figure 4.3: FO Controller Design for IO Model of 2DSFL Robotic Manipulator

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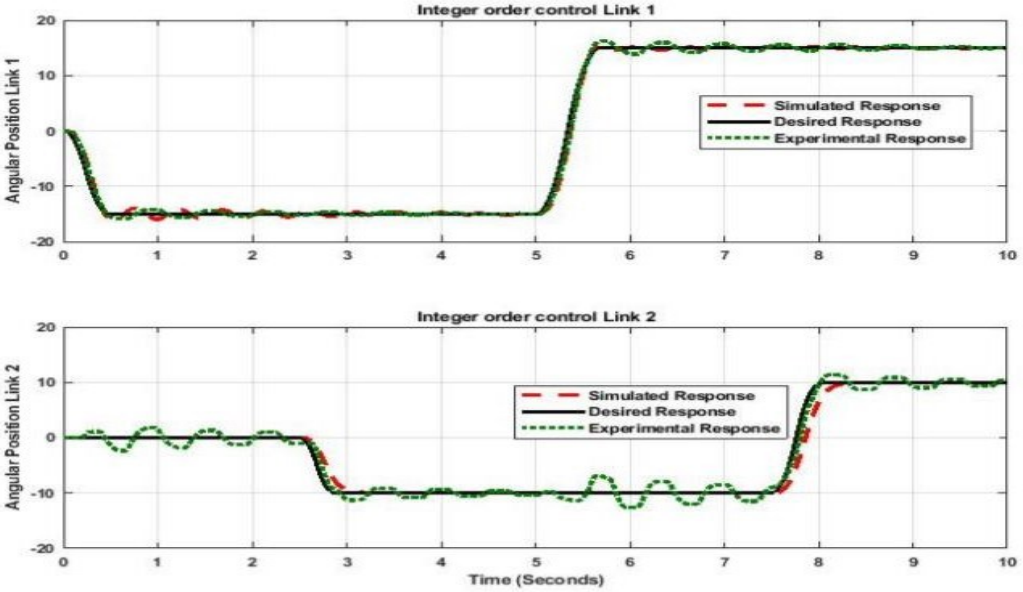

Figure 4.4: IO Controller Design for IO Model of 2DSFL Robotic Manipulator

Figure 4.3 shows the experimental response alongside the simulated response. The 2DSFL's Link 1 and Link 2 are clearly following the target response, as shown in Figure 4.4. Finding stability at the required set point of Link 1 and Link 2 with oscillations takes more time using the IO controller compared to the FO controller, according to the data. The tuned values of P, I, and D are maintained constant while developing the IO controller and FO controller for comparative purposes.

By comparing the findings in Figures 4.3 and 4.4, it is clear that a FO controller, which can be adjusted by varying the values of α and β, provides a more precise control over the response than an IO.

FO Controller Design for IO model of 2DSFJ Robotic Manipulator and Experimental Validation

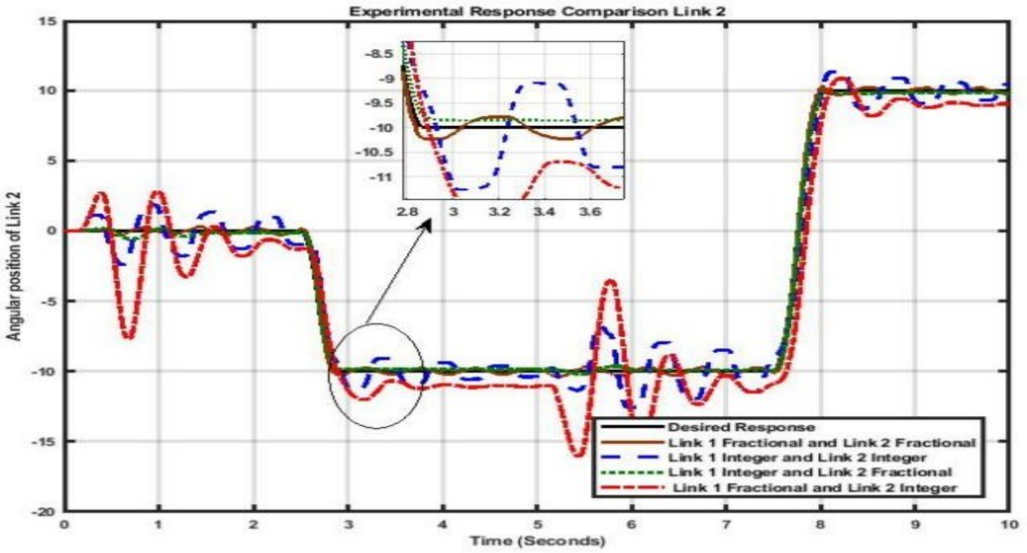

Figure 4.5: Experimental Controlled Response Comparison Link 2

Figure 4.5 shows that the 2DSFJ system consists of two separate joints. Therefore, the controls for the two corners' positions are of separate design. The controller was designed with four situations in mind, each corresponding to an angular position. Here are the items:

1. Joint 2 Controller Fractional and Joint 1 Controller
2. Joint 2 Controller Fractional and Joint 1 Controller
3. Integer Controller Joint and Joint 1 Joint

4.Controller with Joint 1 and 2 Integers

CONCLUSION

When compared to human workers, robot handlers consistently demonstrate superior accuracy and precision across all tasks. Our main objective is to accomplish this

Researchers are aiming to improve the efficiency and usability of robotic manipulators in response to the increasing demand for more accurate manipulators. The FO modelling parameters of a POAC system are determined via an iterative approach. In this study, we evaluate the POAC FO Model using MATLAB and contrast its results with those of the traditional IO Model used in the system. The results of the simulation clearly show that the controlled output of the FO Model has a better transient response than the IO model.

A 2D garage crane system may be FO-modeled via the trial-and-error method. We compare the 2D Gantry Crane FO model to the standard IO model of the same system using MATLAB simulations. The results of the simulation clearly show that the controlled output of the FO Model has a better transient response than the IO model.

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