

# Contents

<b>1</b>	<b>Industrial Robots in Contact-Free Operation</b>	<b>1</b>
1.1	Dynamic Analysis of Rigid Link Robots	1
1.2	Kinematic Analysis of Rigid Link Robots	5
1.3	Dynamic Analysis of Flexible-Link Robots	8
1.4	Kinematic Analysis of Flexible-Link Robots	9
1.5	Control of Rigid-Link Robots in Contact-Free Operation	13
1.6	Control of Flexible-Link Robots in Contact-Free Operation	14
1.6.1	Inverse Dynamics Control of Flexible-Link Robots	14
1.6.2	Energy-Based Control of Flexible Link Robots	16
1.6.3	Adaptive Neural Control of Flexible Manipulators	19
1.6.4	Approximation of the Flexible-Links Dynamics	22
1.7	Simulation of Flexible-Link Robot Control	25
1.7.1	Model-Based Control of Flexible-Link Robots	25
1.7.2	Energy-Based Control	26
1.7.3	Adaptive Neural Control	28
<b>2</b>	<b>Industrial Robots in Compliance Tasks</b>	<b>31</b>
2.1	Impedance Control	31
2.2	Hybrid Position/Force Control	34
2.2.1	Stiffness Identification in Compliance Tasks	35
2.2.2	Application of Robot Hybrid Position/Force Control	37
2.3	Force Control of Flexible-Link Robots	39
2.3.1	Interaction with the Compliant Surface	39
2.3.2	Force Control for Flexible-Link Robots	40
2.4	Simulation of Force Control for Flexible-Link Robots	41

<b>3</b>	<b>Mobile Robots and Autonomous Vehicles</b>	<b>45</b>
3.1	Kinematic Analysis of Mobile Robots	45
3.2	Control of Autonomous Ground Vehicles	46
3.2.1	Differential Flatness for Finite Dimensional Systems	47
3.2.2	Flatness-Based Control of the Autonomous Vehicle	48
3.3	Kinematic and Dynamic Models of Surface Vessels	51
3.3.1	A Generic Kinematic and Dynamic Ship Model	51
3.3.2	Models of Current, Wind and Wave Forces	53
3.3.3	Ship Model for the Dynamic Positioning Problem	54
3.3.4	Ship Actuator Model	54
3.4	Feedback Linearization for Ship Dynamic Positioning	55
3.4.1	Ship Control Using Dynamic Feedback Linearization	55
3.4.2	Estimation of the Unknown Additive Disturbances	56
3.5	Backstepping Control for the Ship Steering Problem	57
3.5.1	The Ship Steering Problem	57
3.5.2	Nonlinear Backstepping	59
3.5.3	Automated Ship Steering Using Backstepping Control	60
3.5.4	Calculation of the SISO Backstepping Nonlinear Controller	61
<b>4</b>	<b>Adaptive Control Methods for Industrial Systems</b>	<b>65</b>
4.1	Adaptive Control of Industrial Systems with Full State Feedback	65
4.1.1	Problem Statement	65
4.1.2	Transformation to a Regulation Problem	67
4.1.3	Approximators of Unknown System Dynamics	68
4.1.4	Lyapunov Stability Analysis in the Case of Full State Feedback	69
4.2	Adaptive Control of Industrial Systems with Output Feedback	71
4.2.1	Transformation to a Regulation Problem	71
4.2.2	Approximation of Unknown System Dynamics	72
4.2.3	Lyapunov Stability Analysis in the Case of Output Feedback	74
4.2.4	Riccati Equation Coefficients and $H_\infty$ Control Robustness	76
4.3	Application to the Control of Electric Motors	77
4.3.1	The DC Motor Model	77
4.3.2	State Feedback Controller of the DC Motor Model	79
4.3.3	State Feedback Controller for the DC Motor	81

4.3.4	Output Feedback Controller for the DC Motor . . . . .	85
4.3.5	Application to the Field-Oriented Induction Motor . . . . .	89
4.4	Application to the Ship Steering Control Problem . . . . .	93
4.5	Application to the Stabilization of Electromechanical Systems . . . . .	96
<b>5</b>	<b>Robust Control Methods for Industrial Systems . . . . .</b>	<b>101</b>
5.1	Robust Control with Sliding-Mode Control Theory . . . . .	101
5.1.1	Sliding-Mode Control . . . . .	101
5.1.2	An Application Example of Sliding-Mode Control . . .	104
5.1.3	Sliding-Mode Control with Boundary Layer . . . . .	105
5.2	Robust Control with Interval Polynomials Theory . . . . .	107
5.2.1	Basics of Kharitonov's Theory . . . . .	107
5.2.2	Extremal Properties of Kharitonov Polynomials . . . .	109
5.3	Application to the Stabilization of Electric Power Systems . . . . .	110
5.3.1	The Problem of Power System Stabilization . . . . .	111
5.3.2	Transfer Function of the Single-Machine Infinite-Bus Model . . . . .	113
5.3.3	Kharitonov's Theory for Power System Stabilization . . . . .	113
<b>6</b>	<b>Filtering and Estimation Methods for Industrial Systems . . . . .</b>	<b>119</b>
6.1	Linear State Observers . . . . .	119
6.2	The Continuous-Time Kalman Filter for Linear Models . . .	120
6.3	The Discrete-Time Kalman Filter for Linear Systems . . . .	121
6.4	The Extended Kalman Filter for Nonlinear Systems . . . . .	122
6.5	Sigma-Point Kalman Filters . . . . .	124
6.6	Particle Filters . . . . .	127
6.6.1	The Particle Approximation of Probability Distributions . . . . .	127
6.6.2	The Prediction Stage . . . . .	128
6.6.3	The Correction Stage . . . . .	128
6.6.4	The Resampling Stage . . . . .	130
6.6.5	Approaches to the Implementation of Resampling . . .	130
6.7	Application of Estimation Methods to Industrial Systems Control . . . . .	133
6.7.1	Kalman Filter-Based Control of Electric Motors . . . .	133
6.7.2	Extended Kalman Filter-Based Control of Electric Motors . . . . .	134
6.7.3	Unscented Kalman Filter-Based Control of Electric Motors . . . . .	137
6.7.4	Particle Filter-Based Control of Electric Motors . . . .	138

<b>7</b>	<b>Sensor Fusion-Based Control for Industrial Systems</b>	141
7.1	Sensor Fusion-Based Control of Industrial Robots	141
7.1.1	The Sensor Fusion Problem	141
7.1.2	Application of EKF and PF for Sensor Fusion	143
7.1.3	Simulation of EKF and PF-Based Sensor Fusion for Industrial Robot Control	145
7.2	Sensor Fusion-Based Control for Mobile Robots	155
7.2.1	Simulation of EKF-Based Control for Mobile Robots	155
7.2.2	Simulation of Particle Filter-Based Mobile Robot Control	161
7.2.3	Simulation of EKF and PF-Based Parallel Parking Control	162
7.2.4	Performance Analysis of EKF and PF-Based Mobile Robot Control	163
7.3	Sensor Fusion-Based Dynamic Ship Positioning	165
7.3.1	EKF and PF-Based Sensor Fusion for the Ship Model	165
7.3.2	Simulation of EKF and PF-Based Ship Dynamic Positioning	168
<b>8</b>	<b>Distributed Filtering and Estimation for Industrial Systems</b>	175
8.1	The Problem of Distributed State Estimation over Sensor Networks	175
8.2	Distributed Extended Kalman Filtering	177
8.2.1	Calculation of Local Extended Kalman Filter Estimations	177
8.2.2	Extended Information Filtering for State Estimates Fusion	180
8.3	Distributed Sigma-Point Kalman Filtering	181
8.3.1	Calculation of Local Unscented Kalman Filter Estimations	181
8.3.2	Unscented Information Filtering for State Estimates Fusion	185
8.4	Distributed Particle Filter	186
8.4.1	Distributed Particle Filtering for State Estimation Fusion	186
8.4.2	Fusion of the Local Probability Density Functions	188
8.5	Simulation Tests	190
8.5.1	Multi-UAV Control with Extended Information Filtering	190
8.5.2	Multi-UAV Control with Distributed Particle Filtering	194

<b>9</b>	<b>Fault Detection and Isolation for Industrial Systems . . . . .</b>	<b>197</b>
9.1	Fault Diagnosis with Statistical Methods . . . . .	197
9.1.1	Residual Generation through Nonlinear System Modelling . . . . .	197
9.1.2	Determination of the Nonlinear Model's Structure . . .	199
9.1.3	Stages of Nonlinear Systems Modeling . . . . .	202
9.2	Fault Threshold Selection with the Generalized Likelihood Ratio . . . . .	203
9.2.1	The Local Statistical Approach to Fault Diagnosis . . .	203
9.2.2	Fault Detection with the Local Statistical Approach . . . . .	204
9.2.3	Fault Isolation with the Local Statistical Approach . . . . .	206
9.2.4	Fault Threshold for Residuals of Unknown Distribution . . . . .	208
<b>10</b>	<b>Application of Fault Diagnosis to Industrial Systems . . . . .</b>	<b>213</b>
10.1	Fault Diagnosis of the Electric Power System . . . . .	213
10.1.1	Cascading Events in the Electric Power Grid . . . . .	213
10.1.2	Electric Power Systems Dynamics . . . . .	216
10.1.3	The Multi-area Multi-machine Electric Power System . . . . .	217
10.1.4	Nonlinear Modeling of the Electric Power System . . .	219
10.2	Fault Diagnosis Tests for the Electric Power System . . . . .	221
10.2.1	Parameters of the Nonlinear Power System Model . . .	221
10.2.2	Efficiency of the Fault Diagnosis Method . . . . .	222
10.3	Fault Diagnosis of Electric Motors . . . . .	224
10.3.1	Failures in Rotating Electrical Machines . . . . .	224
10.3.2	Faults in the DC Motor Control Loop . . . . .	225
10.3.3	Residual Generation with the Use of Kalman Filtering . . . . .	225
10.3.4	Residual Generation with the Use of Particle Filtering . . . . .	226
10.3.5	Fault Diagnosis in Control Loops . . . . .	228
<b>11</b>	<b>Optimization Methods for Motion Planning of Multi-robot Systems . . . . .</b>	<b>231</b>
11.1	Distributed Gradient for Motion Planning of Multi-robot Systems . . . . .	231
11.1.1	Approaches to Multi-robot Motion Planning . . . . .	231
11.1.2	The Distributed Gradient Algorithm . . . . .	233
11.1.3	Kinematic Model of the Multi-robot System . . . . .	233
11.1.4	Cohesion of the Multi-robot System . . . . .	235
11.1.5	Convergence to the Goal Position . . . . .	237
11.1.6	Stability Analysis Using La Salle's Theorem . . . . .	237

11.2	Particle Swarm Theory for Multi-robot Motion Planning ...	239
11.2.1	The Particle Swarm Theory .....	239
11.2.2	Stability of the Particle Swarm Algorithm .....	240
11.3	Evaluation Tests for the Stochastic Search Algorithms.....	242
11.3.1	Convergence towards the Equilibrium .....	242
11.3.2	Tuning of the Stochastic Search Algorithms.....	249
<b>12</b>	<b>Optimization Methods for Target Tracking by</b>	
	<b>Multi-robot Systems.....</b>	<b>253</b>
12.1	Distributed Motion Planning and Filtering in Multi-robot Systems .....	253
12.1.1	Target Tracking in Mobile Sensors Networks .....	253
12.1.2	The Problem of Distributed Target Tracking .....	255
12.1.3	Tracking of the Reference Path by the Target .....	257
12.1.4	Convergence of the Multi-robot System to the Target .....	258
12.2	Simulation Tests .....	259
12.2.1	Target Tracking Using Extended Information Filtering .....	259
12.2.2	Target Tracking Using Unscented Information Filtering .....	262
<b>13</b>	<b>Optimization Methods for Industrial Automation.....</b>	<b>269</b>
13.1	Multi-objective Optimization for Industrial Automation ...	269
13.1.1	The Warehouse Replenishment Problem .....	269
13.1.2	Multi-objective Optimization Problems.....	270
13.1.3	The Pareto-optimality Principles .....	270
13.1.4	Replenishment as a Pareto Optimization Problem ...	272
13.1.5	Approaches to Obtain Pareto-optimal Solutions .....	272
13.1.6	Graphical Representation of Pareto Optimal Solution .....	275
13.2	Genetic Algorithms in the Search of Pareto-optimal Solutions .....	275
13.2.1	Basic Principles of Evolutionary Algorithms .....	275
13.2.2	Evolutionary Algorithms for Multi-objective Optimization .....	276
13.2.3	Control of Diversity of the Pareto-optimal Solutions .....	277
13.2.4	Genetic Algorithm Convergence to Pareto-optimal Solutions .....	280
13.3	A Genetic Algorithm for the Warehouse Replenishment Task .....	280
13.3.1	Constraints of Genetic Algorithms in Ordering Problems .....	280

13.3.2 The Genetic Algorithm for Replenishment Optimization .....	282
13.3.3 Mating Procedure .....	282
13.3.4 Mutation Procedure .....	284
13.3.5 Definition and Tuning of the Cost Function .....	285
13.4 Results on Genetic Algorithm-Based Warehouse Optimization .....	286
13.4.1 Cost Function Tuning through Weights Selection ....	286
13.4.2 Evaluation of the Genetic Algorithm Performance ...	291
<b>14 Machine Learning Methods for Industrial Systems</b>	
<b>Control .....</b>	<b>293</b>
14.1 Model-Free Control of Flexible-Link Robots.....	293
14.1.1 Approaches for Model-Based Control of Flexible-Link Robots .....	293
14.1.2 Approaches for Model-Free Control of Flexible-Link Robots.....	295
14.1.3 Neural Control Using Multi-frequency Basis Functions .....	296
14.2 Neural Control Using Wavelet Basis Functions .....	297
14.2.1 Wavelet Frames .....	297
14.2.2 Dyadic Grid Scaling and Orthonormal Wavelet Transforms .....	298
14.2.3 The Scaling Function and the Multi-resolution Representation .....	299
14.2.4 Examples of Orthonormal Wavelets.....	300
14.2.5 The Haar Wavelet .....	301
14.3 Neural Networks Using Hermite Activation Functions .....	302
14.3.1 Identification with Feed-Forward Neural Networks ...	302
14.3.2 The Gauss-Hermite Series Expansion .....	304
14.3.3 Neural Networks Using 2D Hermite Activation Functions .....	306
14.4 Results on Flexible-Link Control and Vibrations Suppression.....	308
14.4.1 The Flexible-Link Robot Model .....	308
14.4.2 Control Using Hermite Polynomial-Based Neural Networks .....	308
<b>15 Machine Learning Methods for Industrial Systems</b>	
<b>Fault Diagnosis .....</b>	<b>313</b>
15.1 Automata in Fault Diagnosis Tasks .....	313
15.1.1 Fault Diagnosis of Systems with Event-Driven Dynamics .....	313
15.1.2 System Modelling with the Use of Finite Automata .....	314

- 15.1.3 System Modelling with the Use of Fuzzy Automata ..... 316
  - 15.1.4 Monitoring Signals with the Use of Fuzzy Automata ..... 317
  - 15.2 A Fault Diagnosis Approach Based on Fuzzy Automata .... 318
    - 15.2.1 Generation of the Templates String ..... 318
    - 15.2.2 Syntactic Analysis Using Fuzzy Automata ..... 319
    - 15.2.3 Detection of Fault Patterns by the Fuzzy Automata ..... 322
  - 15.3 Simulation Tests of Fault Diagnosis with Fuzzy Automata ..... 324
- 16 Applications of Machine Vision to Industrial Systems.... 327**
  - 16.1 Machine Vision and Imaging Transformations ..... 327
    - 16.1.1 Some Basic Transformations ..... 327
    - 16.1.2 Perspective Transformation ..... 329
    - 16.1.3 Camera Model ..... 334
    - 16.1.4 Camera Calibration ..... 336
    - 16.1.5 Stereo Imaging ..... 337
  - 16.2 Multi Cameras-Based Visual Servoing for Industrial Robots ..... 339
  - 16.3 Distributed Filtering for Sensorless Control ..... 340
    - 16.3.1 Visual Servoing over a Network of Synchronized Cameras ..... 340
    - 16.3.2 Robot's State Estimation through Distributed Filtering ..... 341
  - 16.4 Distributed State Estimation Using the EIF ..... 342
    - 16.4.1 Local State Estimation with Extended Kalman Filtering ..... 342
    - 16.4.2 State Estimation through a Nonlinear Transformation ..... 344
    - 16.4.3 Derivative-Free Kalman Filtering for Nonlinear Systems ..... 345
    - 16.4.4 Fusing Estimations from Local Distributed Filters ... 345
    - 16.4.5 Calculation of the Aggregate State Estimation ..... 347
  - 16.5 Simulation Tests of the Vision-Based Control System ..... 347
    - 16.5.1 Dynamics and Control of the Robotic Manipulator ..... 347
    - 16.5.2 Evaluation of Results on Vision-Based Control ..... 348
  - References ..... 351
- Index ..... 377**