Neural Network Control of Robot Manipulators and Nonlinear Systems

F.L. LEWIS
Automation and Robotics Research Institute
The University of Texas at Arlington

S. JAGANNATHAN
Systems and Controls Research
Caterpillar, Inc., Mossville

A. YEŞİLDİREK
Manager, New Product Development
Depsa, Panama City
## Contents

List of Tables of Design Equations                                       xi
List of Figures                                                          xviii
Series Introduction                                                    xix
Preface                                                                xxi

1 Background on Neural Networks                                         1
   1.1 NEURAL NETWORK TOPOLOGIES AND RECALL                             2
       1.1.1 Neuron Mathematical Model                                    2
       1.1.2 Multilayer Perceptron                                      7
       1.1.3 Linear-in-the-Parameter (LIP) Neural Nets                   10
       1.1.4 Dynamic Neural Networks                                     14
   1.2 PROPERTIES OF NEURAL NETWORKS                                    24
       1.2.1 Classification, Association, and Pattern Recognition       25
       1.2.2 Function Approximation                                     30
   1.3 NEURAL NETWORK WEIGHT SELECTION AND TRAINING                   32
       1.3.1 Direct Computation of the Weights                          33
       1.3.2 Training the One-Layer Neural Network— Gradient Descent   35
       1.3.3 Training the Multilayer Neural Network— Backpropagation   43
       1.3.4 Improvements on Gradient Descent                           53
       1.3.5 Hebbian Tuning                                            56
       1.3.6 Continuous-Time Tuning                                      57
   1.4 REFERENCES                                                      60
   1.5 PROBLEMS                                                        63

2 Background on Dynamic Systems                                         67
   2.1 DYNAMICAL SYSTEMS                                                67
       2.1.1 Continuous-Time Systems                                    68
       2.1.2 Discrete-Time Systems                                      71
   2.2 SOME MATHEMATICAL BACKGROUND                                     75
       2.2.1 Vector and Matrix Norms                                     75
       2.2.2 Continuity and Function Norms                              76
   2.3 PROPERTIES OF DYNAMICAL SYSTEMS                                  77
CONTENTS

2.3.1 Stability ........................................ 78
2.3.2 Passivity .......................................... 80
2.3.3 Observability and Controllability .............. 83

2.4 FEEDBACK LINEARIZATION AND CONTROL SYSTEM DESIGN 86
2.4.1 Input-Output Feedback Linearization Controllers ............. 87
2.4.2 Computer Simulation of Feedback Control Systems .......... 92
2.4.3 Feedback Linearization for Discrete-Time Systems .......... 96

2.5 NONLINEAR STABILITY ANALYSIS AND CONTROLS DESIGN 97
2.5.1 Lyapunov Analysis for Autonomous Systems ............. 97
2.5.2 Controller Design Using Lyapunov Techniques .......... 103
2.5.3 Lyapunov Analysis for Non-Autonomous Systems .......... 106
2.5.4 Extensions of Lyapunov Techniques and Bounded Stability .... 109

2.6 REFERENCES .......................................... 115

2.7 PROBLEMS ............................................ 116

3 Robot Dynamics and Control .................................. 123
3.0.1 Commercial Robot Controllers ......................... 123

3.1 KINEMATICS AND JACOBIANS ..................... 124
3.1.1 Kinematics of Rigid Serial-Link Manipulators .......... 125
3.1.2 Robot Jacobians ................................... 128

3.2 ROBOT DYNAMICS AND PROPERTIES .................. 129
3.2.1 Joint Space Dynamics and Properties ................ 130
3.2.2 State Variable Representations .................... 134
3.2.3 Cartesian Dynamics and Actuator Dynamics .......... 135

3.3 COMPUTED-TORQUE (CT) CONTROL AND COMPUTER SIMULATION .... 136
3.3.1 Computed-Torque (CT) Control .................... 136
3.3.2 Computer Simulation of Robot Controllers ............ 138
3.3.3 Approximate Computed-Torque Control and Classical Joint Control .... 143
3.3.4 Digital Control .................................... 145

3.4 FILTERED-ERROR APPROXIMATION-BASED CONTROL ........ 147
3.4.1 A General Controller Design Framework Based on Approximation .... 154
3.4.2 Computed-Torque Control Variant .................. 156
3.4.3 Adaptive Control .................................. 156
3.4.4 Robust Control .................................... 162
3.4.5 Learning Control .................................. 165

3.5 CONCLUSIONS ........................................... 167
3.6 REFERENCES ........................................... 168
3.7 PROBLEMS ............................................. 169

4 Neural Network Robot Control .................................. 173
4.1 ROBOT ARM DYNAMICS AND TRACKING ERROR DYNAMICS .... 176
4.2 ONE-LAYER FUNCTIONAL-LINK NEURAL NETWORK CONTROLLER .. 179
4.2.1 Approximation by One-Layer Functional-Link NN ........ 180
CONTENTS

4.2.2 NN Controller and Error System Dynamics .................................. 181
4.2.3 Unsupervised Backpropagation Weight Tuning ............................... 182
4.2.4 Augmented Unsupervised Backpropagation Tuning—Removing the PE Condition ................................................................. 187
4.2.5 Functional-Link NN Controller Design and Simulation Example .......... 190
4.3 TWO-LAYER NEURAL NETWORK CONTROLLER ................................. 191
4.3.1 NN Approximation and the Nonlinearity in the Parameters Problem ................................................................. 194
4.3.2 Controller Structure and Error System Dynamics ............................. 196
4.3.3 Weight Updates for Guaranteed Tracking Performance ..................... 198
4.3.4 Two-Layer NN Controller Design and Simulation Example ................. 206
4.4 PARTITIONED NN AND SIGNAL PREPROCESSING .................................. 206
4.4.1 Partitioned NN ............................................................................. 206
4.4.2 Preprocessing of Neural Net Inputs ............................................... 209
4.4.3 Selection of a Basis Set for the Functional-Link NN ......................... 209
4.5 PASSIVITY PROPERTIES OF NN CONTROLLERS ................................. 212
4.5.1 Passivity of the Tracking Error Dynamics ....................................... 212
4.5.2 Passivity Properties of NN Controllers ......................................... 213
4.6 CONCLUSIONS .................................................................................. 216
4.7 REFERENCES ..................................................................................... 217
4.8 PROBLEMS ....................................................................................... 219

5 Neural Network Robot Control: Applications and Extensions .................. 221
5.1 FORCE CONTROL USING NEURAL NETWORKS ................................. 222
5.1.1 Force Constrained Motion and Error Dynamics ............................... 223
5.1.2 Neural Network Hybrid Position/Force Controller ........................... 225
5.1.3 Design Example for NN Hybrid Position/Force Controller ............... 232
5.2 ROBOT MANIPULATORS WITH LINK FLEXIBILITY, MOTOR DYNAMICS, AND JOINT FLEXIBILITY ................................................................. 233
5.2.1 Flexible-Link Robot Arms ................................................................ 233
5.2.2 Robots with Actuators and Compliant Drive Train Coupling .............. 238
5.2.3 Rigid-Link Electrically-Driven (RLED) Robot Arms ............................ 244
5.3 SINGULAR PERTURBATION DESIGN .................................................. 245
5.3.1 Two-Time-Scale Controller Design ................................................. 246
5.3.2 NN Controller for Flexible-Link Robot Using Singular Perturbations ........ 249
5.4 BACKSTEPPING DESIGN .................................................................... 258
5.4.1 Backstepping Design ..................................................................... 258
5.4.2 NN Controller for Rigid-Link Electrically-Driven Robot Using Backstepping ................................................................. 262
5.5 CONCLUSIONS .................................................................................. 267
5.6 REFERENCES ..................................................................................... 270
5.7 PROBLEMS ....................................................................................... 272
# 6 Neural Network Control of Nonlinear Systems

<table>
<thead>
<tr>
<th>Section</th>
<th>Title</th>
<th>Page</th>
</tr>
</thead>
<tbody>
<tr>
<td>6.1</td>
<td>SYSTEM AND TRACKING ERROR DYNAMICS</td>
<td>278</td>
</tr>
<tr>
<td>6.1.1</td>
<td>Tracking Controller and Error Dynamics</td>
<td>279</td>
</tr>
<tr>
<td>6.1.2</td>
<td>Well-Defined Control Problem</td>
<td>281</td>
</tr>
<tr>
<td>6.2</td>
<td>CASE OF KNOWN FUNCTION $g(x)$</td>
<td>281</td>
</tr>
<tr>
<td>6.2.1</td>
<td>Proposed NN Controller</td>
<td>282</td>
</tr>
<tr>
<td>6.2.2</td>
<td>NN Weight Tuning for Tracking Stability</td>
<td>283</td>
</tr>
<tr>
<td>6.2.3</td>
<td>Illustrative Simulation Example</td>
<td>286</td>
</tr>
<tr>
<td>6.3</td>
<td>CASE OF UNKNOWN FUNCTION $g(x)$</td>
<td>287</td>
</tr>
<tr>
<td>6.3.1</td>
<td>Proposed NN Controller</td>
<td>287</td>
</tr>
<tr>
<td>6.3.2</td>
<td>NN Weight Tuning for Tracking Stability</td>
<td>289</td>
</tr>
<tr>
<td>6.3.3</td>
<td>Illustrative Simulation Examples</td>
<td>296</td>
</tr>
<tr>
<td>6.4</td>
<td>CONCLUSIONS</td>
<td>301</td>
</tr>
<tr>
<td>6.5</td>
<td>REFERENCES</td>
<td>303</td>
</tr>
</tbody>
</table>

# 7 NN Control with Discrete-Time Tuning

<table>
<thead>
<tr>
<th>Section</th>
<th>Title</th>
<th>Page</th>
</tr>
</thead>
<tbody>
<tr>
<td>7.1</td>
<td>BACKGROUND AND ERROR DYNAMICS</td>
<td>306</td>
</tr>
<tr>
<td>7.1.1</td>
<td>Neural Network Approximation Property</td>
<td>306</td>
</tr>
<tr>
<td>7.1.2</td>
<td>Stability of Systems</td>
<td>308</td>
</tr>
<tr>
<td>7.1.3</td>
<td>Tracking Error Dynamics for a Class of Nonlinear Systems</td>
<td>308</td>
</tr>
<tr>
<td>7.2</td>
<td>ONE-LAYER NEURAL NETWORK CONTROLLER DESIGN</td>
<td>310</td>
</tr>
<tr>
<td>7.2.1</td>
<td>Structure of the One-layer NN Controller and Error System Dynamics</td>
<td>311</td>
</tr>
<tr>
<td>7.2.2</td>
<td>One-layer Neural Network Weight Updates</td>
<td>312</td>
</tr>
<tr>
<td>7.2.3</td>
<td>Projection Algorithm</td>
<td>316</td>
</tr>
<tr>
<td>7.2.4</td>
<td>Ideal Case: No Disturbances or NN Reconstruction Errors</td>
<td>321</td>
</tr>
<tr>
<td>7.2.5</td>
<td>One-layer Neural Network Weight Tuning Modification for Relaxation of Persistency of Excitation Condition</td>
<td>321</td>
</tr>
<tr>
<td>7.3</td>
<td>MULTILAYER NEURAL NETWORK CONTROLLER DESIGN</td>
<td>327</td>
</tr>
<tr>
<td>7.3.1</td>
<td>Structure of the NN Controller and Error System Dynamics</td>
<td>330</td>
</tr>
<tr>
<td>7.3.2</td>
<td>Multilayer Neural Network Weight Updates</td>
<td>331</td>
</tr>
<tr>
<td>7.3.3</td>
<td>Projection Algorithm</td>
<td>338</td>
</tr>
<tr>
<td>7.3.4</td>
<td>Multilayer Neural Network Weight Tuning Modification for Relaxation of Persistency of Excitation Condition</td>
<td>340</td>
</tr>
<tr>
<td>7.4</td>
<td>PASSIVITY PROPERTIES OF THE NN</td>
<td>350</td>
</tr>
<tr>
<td>7.4.1</td>
<td>Passivity Properties of the Tracking Error System</td>
<td>350</td>
</tr>
<tr>
<td>7.4.2</td>
<td>Passivity Properties of One-layer Neural Networks and the Closed-Loop System</td>
<td>352</td>
</tr>
<tr>
<td>7.4.3</td>
<td>Passivity Properties of Multilayer Neural Networks</td>
<td>353</td>
</tr>
<tr>
<td>7.5</td>
<td>CONCLUSIONS</td>
<td>354</td>
</tr>
<tr>
<td>7.6</td>
<td>REFERENCES</td>
<td>354</td>
</tr>
<tr>
<td>7.7</td>
<td>PROBLEMS</td>
<td>356</td>
</tr>
</tbody>
</table>