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CONTENTS

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Feedforward and Feedback Kinematics Controller for Wheeled Mobile Robot Trajectory Tracking	178
<i>Muhammad Asif, Muhammad Junaid Khan, Muhammad Safwan, and Muhammad Rehan</i>	
Control of Structural Acoustic Radiation Based on Topography Optimization	183
<i>Chu. Khac Trung and Yu. Dejie</i>	
Conceptual Design of Spherical Vehicle System for Future Transportation.....	191
<i>Chun-Hsien Ho, Chen-Kai Wu, Jia-Ying Tu, and Shang-Kai Hsu</i>	
Docking Process Analysis in Self-repairing Robots.....	196
<i>Yanqiong Fei, Pengwei Gong, and Libo Song</i>	
Direct MRAS Based an Adaptive Control System for a Two-Wheel Mobile Robot.....	201
<i>Nguyen Duy Cuong, Gia Thi Dinh, and Tran Xuan Minh</i>	
MRAS Based LFFC for a Two-Link Rigid Robot Arm	208
<i>Nguyen Duy Cuong and Tran Xuan Minh</i>	
Compact Variable Stiffness Joint with Force Sensing Ability-Application to Classify Contact Surfaces.....	215
<i>Shinya Kajikawa and Aruto Suzuki</i>	
Frequency-weighted Model Reduction Using Firefly Algorithm.....	222
<i>Tomohiro Hachino, Koichi Tanigawa, Hitoshi Takata, Seiji Fukushima, and Yasutaka Igarashi</i>	
Design and Implementation of a Fault Diagnosis and Fail Safe on an Electronic Parking Systems.....	228
<i>Donghoon Ban, Taeyoung Lee, and Sungho Jin</i>	
Controlling Voltages and Reduction of Real Power Loss in Power System by Using Crossbreed Spiral Dynamics Bacterial Chemotaxis Algorithm.....	233
<i>K. Lenin and B. Ravindranath Reddy</i>	
An Overview in Energy Conservation of Thermal Storage Techniques for Solar Thermal Applications.....	237
<i>Abdullah M. Al-Shaalan and Tauqeer Ahmed Shaikh</i>	
Target Allocation Study for Formation Ship-To-Air Missile System Based on the Missile Fire Zone Division	241
<i>Jihua Dou and Shouquan Dong</i>	
Influencing Factors for Use of Unmanned Aerial Systems in Support of Aviation Accident and Emergency Response.....	246
<i>Brent Terwilliger, Dennis Vincenzi, David Ison, Kenneth Witcher, David Thirtyacre, and Adeel Khalid</i>	
Stereo Camera-based Intelligence Surveillance System.....	253
<i>Junghwan Ko and Jungsuk Lee</i>	
Lane Detection Using Median Filter, Wiener Filter and Integrated Hough Transform	258
<i>Sukriti Srivastava, Manisha Lumb, and Ritika Singal</i>	

Feedforward and Feedback Kinematics Controller for Wheeled Mobile Robot Trajectory Tracking

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Abstract—In this paper, trajectory tracking of a differential drive nonholonomic mobile robot is presented. In addition to the complex relations of the control system, the nonholonomic system adds complexity to the system which has been solved using the feed-forward and feedback fuzzy logic controllers. An innovative scheme has been developed to track the reference trajectory in the presence of model uncertainties and disturbances. The performance comparison of the proposed controller is done with the standard backstepping controller and the simulation results show that the developed controller is best suited for the tracking trajectory problems.

Index Terms—WMR; trajectory tracking; kinematics; fuzzy logic

I. INTRODUCTION

In the recent years, the tracking and control of wheeled mobile robots (WMR) has received lots of attentions from the robotic community because of many applications includes security, transportation, inspection and exploration. Due to the mechanical design and configuration, the WMR is classified into two categories: holonomic and nonholonomic. Holonomic robots are those in which the controllable degree of freedom is equal to total degree of freedom, whereas nonholonomic robots have less controllable degree of freedom compare to total degree of freedom and have restricted mobility [1]-[3]. Therefore, the controlling and trajectory tracking of nonholonomic WMR has been considered more challenging problem and many researchers proposed various controllers [3].

In case of trajectory tracking, the WMR has to follow a reference path either predefined or obtained from the other WMR. The standard technique to solve this problem is to design a kinematics controller which generates desired velocities based on position errors compare to reference position. Various researchers have proposed the kinematic controller for trajectory tracking based on “perfect velocity tracking” using e.g. fuzzy control [4], neural network [5], adaptive feedback [6],

input-output feedback linearization [7], [8] and backstepping [1], and so on. However, the presented works have poor transient and steady state characteristics in the presence of disturbance and model uncertainties. In addition, most of the works use simple trajectories with constant linear and angular velocities. In this research work, an innovative kinematic controller is proposed for trajectory following to generate the kinematic velocities. The controller structure uses feed-forward and feedback controllers. The feed-forward controller is designed based on reference positions and velocities along with error propagation model, whereas the feedback controller is designed using fuzzy logic. The effectiveness of the designed controller is validated by computer simulations. In addition, the performance and effectiveness of the proposed scheme is compared with standard kinematic controller. The lamniscate curve reference trajectory is used for non-constant linear and angular velocities.

The main motivation of this work is to design a controller which can model the system with poor transient and steady state error in the presence of disturbances and model uncertainties. An innovative feed-forward and feedback controller is designed to cater above mentioned issues. Most importantly a difficult trajectory is chosen to test the controller so that the effectiveness of the controller may be verified. A comprehensive program using MATLAB (Simulink) is developed to test the feasibility of entire work which would be presented later. In this paper, a Fuzzy logic controller is used which is more dynamic and can model uncertainties in a better fashion. The novelty of this work is its comparison with the back stepping controller and the results shows the effectiveness of the proposed controller.

The breakup of the further work is structured as follows: Section II discusses the modeling of the WMR. Section III presents the designing of feed-forward and feedback kinematic controller. The simulation results are presented in Section IV. Finally Section V provides the conclusion.

II. KINEMATIC MODELING OF WMR

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