

HARDWARE-IN-THE-LOOP STUDY OF A
HYBRID ACTIVE FORCE CONTROL SCHEME
OF AN UPPER-LIMB EXOSKELETON FOR
PASSIVE STROKE REHABILITATION

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Doctor of Philosophy

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SUPERVISOR'S DECLARATION

I hereby declare that I have checked this thesis and in my opinion, this thesis is adequate in terms of scope and quality for the award of the degree of Doctor of Philosophy.

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STUDENT'S DECLARATION

I hereby declare that the work in this thesis is based on my original work except for quotations and citations which have been duly acknowledged. I also declare that it has not been previously or concurrently submitted for any other degree at Universiti Malaysia Pahang or any other institutions.

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ABSTRAK

Beban strok memerlukan penggunaan teknologi robotik untuk mengurangkan ketidakupayaan ahli fisioterapi untuk menampung permintaan yang semakin meningkat untuk pemulihan mangsa strok. Latihan gerakan pasif yang berterusan menunjukkan bahawa pesakit strok boleh mendapatkan semula pergerakan mereka. Tambahan pula, bentuk pemulihan ini adalah penting terutamanya dalam fasa neurorehabilitasi akut dan sub-akut. Tesis ini bertujuan untuk menilai satu kelas skim kawalan yang tegap iaitu kawalan daya aktif (AFC) pada dua darjah kebebasan rangka luar anggota atas yang dapat mengimbangi gangguan yang timbul daripada berat bahagian atas yang berbeza dan unik untuk setiap individu tanpa perlu untuk penalaan semula. Untuk menilai keberkesanan pengawal yang dicadangkan, siasatan simulasi dilakukan. Dinamik sistem yang di nilai itu diperolehi berdasarkan rumus Euler-Lagrange dengan memasukkan pengukuran antropometri pada anggota atas manusia. Keberkesanan pengawal yang dicadangkan, iaitu senibina terbitan berkadaran (PD) AFC (PDAFC) klasik yang dioptimumkan melalui logik kabur (FL), rangkaian neural buatan (ANN), pengoptimuman kawanan partikel (PSO) dan simulasi penapisan Kalman (SKF) terhadap pengendalian PD klasik dalam mengurangkan konfigurasi gangguan yang berbeza (tiada gangguan, gangguan berterusan 30 N.m. dan gangguan harmonik 30 N.m. pada kekerapan 10 Hz pada kelajuan yang berbeza, iaitu perlahan (0.375 rad/s), sederhana (0.430 rad/s) dan pantas (0.502 rad/s) trajektori pemulihan yang lazim untuk sendi bahu dan siku dinilai. Hasil keputusan dari penyiasatan simulasi menunjukkan bahawa skim PDSKF AFC adalah lebih baik berbanding semua skim yang dinilai, terutamanya skim kawalan PD klasik. Satu model berasaskan data dibangunkan berdasarkan prototaip rangka luar anggota atas manusia yang dibina. Satu simulasi perkakasan-dalam-gelung dijalankan untuk menilai gandaan yang bersesuaian bagi parameter PD dan inersia AFC yang diperolehi melalui algoritma SKF. Hasil keputusan eksperimen menunjukkan bahawa skim PDSKF AFC mampu mengimbangi gangguan yang disebabkan oleh jisim lengan atas (2 kg) dan lengan bawah boneka (1.5 kg) masing-masing kepada prototaip rangka luar berbanding dengan skim PD klasik.

ABSTRACT

The burden of stroke has necessitated the employment of robotics to mitigate the inability of physiotherapists to cope with the increasing demand for rehabilitation by stroke survivors. Continuous passive motion training has been demonstrated to be able to allow stroke patients to regain their mobility. Furthermore, this form of rehabilitation is non-trivial particularly in the acute and sub-acute phase of neurorehabilitation. This thesis aims at evaluating a class of robust control scheme, namely active force control (AFC) on a two degrees of freedom upper-limb exoskeleton that is able to compensate disturbances arising from different upper-limb weights that are unique for different individuals without the need for further re-tuning. In order to evaluate the efficacy of the proposed controller, a simulation investigation was performed. The dynamics of the system are derived based on the Euler-Lagrange formulation by incorporating anthropometric measurements of the human upper limb. The efficacy of the proposed controllers, namely classical Proportional-Derivative AFC (PDAFC) architecture optimised by means of fuzzy logic (FL), artificial neural network (ANN), particle swarm optimisation (PSO) and simulated Kalman filter (SKF) against classical PD control in mitigating different disturbance configurations (no disturbance, constant disturbance of 30 N.m. and harmonic disturbance of 30 N.m. at a frequency of 10 Hz at different speeds, i.e., slow (0.375 rad/s), medium (0.430 rad/s) and fast (0.502 rad/s) of a typical rehabilitation trajectory for the shoulder and elbow joints were evaluated. It is shown from the simulation investigation that the PDSKFAFC scheme is better in comparison to all the evaluated schemes, particularly the classical PD control scheme. A data-driven model is developed based on the exoskeleton prototype built. A hardware-in-the-loop simulation is carried out to evaluate the appropriate gains of both the PD and the AFC inertial parameter gained that is tuned via the SKF algorithm. It is demonstrated through the experimental works, that the PDSKFAFC scheme is able to compensate against the disturbance attributed by the attached mannequin mass of the upper arm (2 kg) and forearm (1.5 kg), respectively to the exoskeleton prototype in comparison the classical PD scheme.

TABLE OF CONTENT

DECLARATION	
TITLE PAGE	
ACKNOWLEDGEMENTS	ii
ABSTRAK	iii
ABSTRACT	iv
TABLE OF CONTENT	v
LIST OF TABLES	ix
LIST OF FIGURES	x
LIST OF SYMBOLS	xv
LIST OF ABBREVIATIONS	xvii
CHAPTER 1 INTRODUCTION	1
1.1 Research Motivation	1
1.2 Problem Statement	3
1.3 Aim and Objectives	4
1.4 Research Scope	4
1.5 Thesis Layout	4
CHAPTER 2 LITERATURE REVIEW	6
2.1 Introduction	6
2.2 Stroke	6
2.3 Post-Stroke Rehabilitation	7
2.4 Upper-limb Biomechanics	9

2.5	Robotic-Assisted Therapy for the Upper-limb	10
2.6	Related Studies on the Control of Upper-limb Exoskeletons for Passive Rehabilitation Therapy	12
2.7	Active Force Control (AFC)	22
2.8	Summary	37
CHAPTER 3 METHODOLOGY		39
3.1	Introduction	39
3.2	Phases of the Study	39
3.3	Development of the Exoskeleton	41
3.3.1	Actuator	41
3.3.2	Sensors	42
3.3.3	Motor Driver and Data Acquisition System	43
3.3.4	Materials and Design	44
3.4	Summary	46
CHAPTER 4 MODELLING AND SIMULATION		47
4.1	Introduction	47
4.2	Upper-limb Dynamics	47
4.3	Proportional-Derivative Controller	50
4.4	Active Force Control	53
4.4.1	Fuzzy Logic	54
4.4.2	Artificial Neural Network	57
4.4.3	Particle Swarm Optimisation	63
4.4.4	Simulated Kalman Filter	66
4.5	Simulation Results and Discussion	72
4.6	Summary of the Findings	81

CHAPTER 5 DATA-DRIVEN MODELLING AND EXPERIMENTAL WORKS	85
5.1 Introduction	85
5.2 Data-driven Modelling	85
5.3 Hardware in the Loop (HIL) Simulations	90
5.4 Experimental Works	93
5.4.1 Elbow Joint	93
5.4.2 Shoulder Joint	97
5.5 Summary of Findings	99
CHAPTER 6 CONCLUSION AND RECOMMENDATION	100
6.1 Introduction	100
6.2 Summary of the Main Findings	100
6.2.1 Objective 1: The Design of the Proposed Control Scheme	100
6.2.2 Objective 2: Simulation Investigation of the Proposed Control Schemes	101
6.2.3 Objective 3: Data-driven Modelling and Experimental Works	101
6.3 Contribution of Study	102
6.4 Recommendation	102
REFERENCES	104
APPENDIX A TORQUE ESTIMATION	118
APPENDIX B ACTUATOR SPECIFICATION	120
APPENDIX C SENSORS	121
APPENDIX D CAD DRAWINGS	124
APPENDIX E ANN TRAINING	128

APPENDIX F SIMULINK MODEL	129
APPENDIX G ANOVA	130
APPENDIX H LIST OF PUBLICATIONS	135

LIST OF TABLES

Table 2.1	Average movable ranges of the upper-limb	10
Table 2.2	Summary of upper limb exoskeleton systems that employ the passive control approach	18
Table 2.3	Summary of the utilisation of the AFC scheme of different applications	33
Table 3.1	PC specifications	40
Table 4.1	Modelling parameters	50
Table 4.2	PD gains for both shoulder and elbow joints	51
Table 4.3	Joint angle variables for θ_1 and θ_2	57
Table 4.4	Constant variables for x_1 and x_2	57
Table 4.5	PSO parameters	66
Table 4.6	SKF parameters	70
Table 4.7	Tracking error measurements for slow speed (0.375 rad/s)	75
Table 4.8	Tracking error measurements for medium speed (0.430 rad/s)	79
Table 4.9	Tracking error measurements for fast speed (0.502 rad/s)	83
Table 5.1	Estimation and validation performance of the shoulder and elbow system	88
Table 5.2	Tracking error performance	91
Table 5.3	Error metrics for low speed (0.375 rad/s)	93
Table 5.4	Error metrics for medium speed (0.43 rad/s)	93
Table 5.5	Error metrics for fast speed (0.502 rad/s)	93
Table 5.6	ANOVA analysis	94
Table 5.7	Error metrics for shoulder joint	97

LIST OF FIGURES

Figure 1.1	Mortality and morbidity statistics of stroke cases in Malaysia from 2009 to 2013	1
Figure 1.2	Probabilistic projections of the Malaysian population of the age of 60 years and above	2
Figure 2.1	Types and main risk factors of stroke.	7
Figure 2.2	Neurorehabilitation timeline	8
Figure 2.3	Human upper-limb anatomy	9
Figure 2.4	(a) Main movements (degrees of freedom) of the upper-limb (b) Human body anatomical planes	10
Figure 2.5	Robotic rehabilitation devices (a) end-effector-based (b) exoskeleton-based	11
Figure 2.6	A schematic diagram of the AFC scheme	23
Figure 2.7	Performance of the AFC algorithm in the wake of disturbance	29
Figure 3.1	Phases of the Study	41
Figure 3.2	DC brushless motor (MO-PW-CR)	41
Figure 3.3	Industrial grade potentiometer (53C320K)	42
Figure 3.4	Current sensor (BB-ACS756).	43
Figure 3.5	Motor Driver (MD30C)	43
Figure 3.6	Arduino Mega 2560	44
Figure 3.7	A schematic configuration of the mechatronics system	44
Figure 3.8	Exoskeleton's (a) upper arm (b) forearm	45
Figure 3.9	The upper-limb exoskeleton system	46
Figure 4.1	Rigid links that mimic the human upper-limb	47
Figure 4.2	Predefine trajectories for rehabilitating the shoulder and elbow joints	52
Figure 4.3	PD with AFC scheme for the control of the upper-limb exoskeleton	53

Figure 4.4	Fuzzy Concept	54
Figure 4.5	Fuzzy based estimated inertia acquisition (Simulink)	55
Figure 4.6	The membership function for (a) shoulder joint, θ_1 (b) constant, x_1 (c) elbow joint, θ_2 (d) constant, x_2	56
Figure 4.7	The perceptron model	58
Figure 4.8	MLP feedforward network	58
Figure 4.9	ANN based estimated inertia acquisition (Simulink)	60
Figure 4.10	The correlation between output and target of the ANN engine for the shoulder joint (a) in training step, (b) in validation step, (c) in test step and (d) in overall. T is target values; Y is predicted output by model; and R correlation coefficient between the output of model and target values.	61
Figure 4.11	The correlation between output and target of the ANN engine for the elbow joint (a) in training step, (b) in validation step, (c) in test step and (d) in overall. T is target values; Y is predicted output by model; and R correlation coefficient between output of model and target values.	62
Figure 4.12	Schematic movement of a particle	64
Figure 4.13	The PSO algorithm	65
Figure 4.14	Estimated inertial parameters via the PSO algorithm	66
Figure 4.15	The SKF algorithm	69
Figure 4.16	Estimated inertial parameters via the SKF algorithm	70
Figure 4.17	RMSE comparison between control algorithms at slow speed (0.375 rad/s) (a) shoulder tracking error without disturbance (b) elbow tracking error without disturbance (d) shoulder tracking error with constant disturbance (e) elbow tracking error with constant disturbance (f) shoulder tracking error with harmonic disturbance (g) elbow tracking error with harmonic disturbance	72

- Figure 4.18 Tracking error response comparison between the classical PD and the PDSKFAFC at slow speed (0.375 rad/s) (a) shoulder tracking error without disturbance (b) elbow tracking error without disturbance (d) shoulder tracking error with constant disturbance (e) elbow tracking error with constant disturbance (f) shoulder tracking error with harmonic disturbance (g) elbow tracking error with harmonic disturbance 74
- Figure 4.19 RMSE comparison between control algorithms at medium speed (0.430 rad/s) (a) shoulder tracking error without disturbance (b) elbow tracking error without disturbance (d) shoulder tracking error with constant disturbance (e) elbow tracking error with constant disturbance (f) shoulder tracking error with harmonic disturbance (g) elbow tracking error with harmonic disturbance 76
- Figure 4.20 Tracking error response comparison between the classical PD and the PDSKFAFC at medium speed (0.430 rad/s) (a) shoulder tracking error without disturbance (b) elbow tracking error without disturbance (d) shoulder tracking error with constant disturbance (e) elbow tracking error with constant disturbance (f) shoulder tracking error with harmonic disturbance (g) elbow tracking error with harmonic disturbance 78
- Figure 4.21 RMSE comparison between control algorithms at fast speed (0.502 rad/s) (a) shoulder tracking error without disturbance (b) elbow tracking error without disturbance (d) shoulder tracking error with constant disturbance (e) elbow tracking error with constant disturbance (f) shoulder tracking error with harmonic disturbance (g) elbow tracking error with harmonic disturbance 80
- Figure 4.22 Tracking error response comparison between the classical PD and the PDSKFAFC at fast speed (0.502 rad/s) (a) shoulder tracking error without disturbance (b) elbow tracking error without disturbance (d) shoulder tracking error with constant disturbance (e) elbow tracking error with constant disturbance (f) shoulder tracking

	error with harmonic disturbance (g) elbow tracking error with harmonic disturbance	82
Figure 5.1	Input-output of the shoulder joint	86
Figure 5.2	Input-output of the elbow joint	86
Figure 5.3	Estimation stage elbow system	87
Figure 5.4	Validation stage elbow system	88
Figure 5.5	Estimation stage shoulder system	88
Figure 5.6	Validation stage shoulder system	89
Figure 5.7	Zero-pole location of the elbow system	89
Figure 5.8	Zero-pole location of the shoulder system	90
Figure 5.9	Convergence curve (a) IN_1 (b) IN_2	92
Figure 5.10	(a) Shoulder joint trajectory tracking (b) Shoulder joint tracking error (c) Elbow joint trajectory tracking (d) Elbow joint tracking error	92
Figure 5.11	Comparison between the classical PD and the PDSKFAFC for elbow joint at slow speed (0.375 rad/s) (a) Trajectory tracking without disturbance (b) Tracking error without disturbance (c) Trajectory tracking with disturbance (d) Tracking error with disturbance	95
Figure 5.12	Comparison between the classical PD and the PDSKFAFC for elbow joint at medium speed (0.43 rad/s) (a) Trajectory tracking without disturbance (b) Tracking error without disturbance (c) Trajectory tracking with disturbance (d) Tracking error with disturbance	96
Figure 5.13	Comparison between the classical PD and the PDSKFAFC for elbow joint at fast speed (0.502 rad/s) (a) Trajectory tracking without disturbance (b) Tracking error without disturbance (c) Trajectory tracking with disturbance (d) Tracking error with disturbance	96

Figure 5.14 Comparison between the classical PD and the PDSKFAFC for shoulder joint with disturbance at (a) Trajectory tracking for slow speed (0.375 rad/s) (b) Tracking error for slow speed (0.375 rad/s) (c) Trajectory tracking for medium speed (0.430 rad/s) (d) Tracking error for medium speed (0.375 rad/s) (e) Trajectory tracking for fast speed (0.502 rad/s) (f) Tracking error for slow speed (0.502 rad/s) (g) Trajectory tracking for step response (h) Tracking error for step response.

98

LIST OF SYMBOLS

IN	Estimated Mass/ Estimated Inertial Matrix
θ_1	Shoulder joint angle
θ_2	Elbow joint angle
L	Lagrangian
K	Kinetic energy
P	Potential energy
τ_d	Disturbance torque
g	Gravity
J	Mass moment of inertia
m	Mass
e	Angular position error
\dot{e}	The rate of angular position error
K_d	Derivative gain
K_p	Proportional gain
\ddot{i}	Measured acceleration signal
τ	Measured actuation torque
x	Constant
b	Bias
R	Correlation coefficient
R^2	Coefficient of determination
s_i^{k+1}	Next particle position
s_i^k	Current particle position
v_i^{k+1}	Velocity of particle
r_1	Random number
r_2	Random number
c_1	Cognitive learning factor
c_2	Social learning factor
pbest	Personal best
gbest	Global best
ω	Inertia weight

k	k -th generation
n	Swarm size
P	Error covariance estimate
Q	Process noise
R	Measurement Noise
$Z_i(t)$	Measurement of each individual agent
$K(t)$	Kalman gain
t	Iteration
I	Current
K_t	Torque constant
IN^*	Modified IN

LIST OF ABBREVIATIONS

AFC	Active Force Control
ANN	Artificial Neural Network
CEACS	Combined Energy and Attitude Control System
CTC	Computed Torque Control
FL	Fuzzy Logic
HIL	Hardware-in-the-Loop
MAE	Maximum of the Absolute Error
MSE	Mean Squared Error
MSD	Means and Standard Deviations
mSMERL	Modified Sliding Mode Exponential Reaching Law
PC	Personal Computer
PID	Proportional-Integral-Derivative
PD	Proportional-Derivative
PI	Proportional-Integral
PSO	Particle Swarm Optimisation
RAC	Resolved Acceleration Control
RMSE	Root Mean Squared Error
SKF	Simulated Kalman Filter
SMC	Sliding Mode Control
WAM	Whole Arm Manipulator

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