International Journal of Recent Technology and Engineering (IJRTE)
ISSN: 2277-3878 (Online), Volume-12 Issue-4, November 2023

Obstacle Avoidance Trajectory Planning for Robotic Arm based on Genetic Algorithm

Masood Usama, Xianhua Li, Haohao Yu, Yamin Iqra

Abstract: ***For the problem of obstacle avoidance trajectory planning of a robot arm, a robot arm obstacle avoidance method based on a genetic algorithm is proposed. It is based on the two problems that the motion process can avoid obstacles and the motion process is more stable and efficient. First, the motion of each joint is planned as a sixth-degree polynomial, and the coefficients of the sixth-degree term are set as the pending parameters, and the motion of each joint is changed by changing the pending parameters. Then, the fitness function is then constructed by calculating the collision detection, angular velocity limit detection, acceleration limit detection, and the total trajectory length and rotation angle for each joint. Finally, the fitness function is optimised using a genetic algorithm to obtain smooth, continuous, and collision-free trajectories. Matlab simulation experiments show that this method can obtain the optimal or suboptimal trajectory without collision.***

Keywords: Genetic Algorithm; Obstacle Avoidance; Robotic Arm; Trajectory Planning

I. INTRODUCTION

With the continuous progress of science, robotics is beginning to be used in a variety of fields, and the main purpose of the birth of robotics is to replace human beings to perform some dangerous, complex, and heavy tasks, and improve work efficiency. In order to make the robot can work more safely and efficiently. Firstly, the robotic arm must be controlled to avoid all obstacles rather than a single-end position. Secondly, the speed and acceleration of each joint should be continuous and not too large. Finally, the amount of movement of the robot arm during operation should be minimized. Currently, a large number of researchers have studied the obstacle avoidance path planning of robot arms. In the literature [1], the A* algorithm, a global path search algorithm, is used. It maps the Cartesian space onto the joint space, which in turn finds the free motion space of the robot arm, and then uses the A* algorithm for path search. Literature [2-3][10] uses the artificial potential field method. This is the classical algorithm and the article improves the artificial potential field method. The algorithm is to apply a suction force to the target so that the path attracts to reach the target point, and a repulsion force to the obstacle so that the path repels to avoid the obstacle. The literature [4-5], on the other hand, used the random search tree algorithm. With the development of artificial intelligence algorithms, researchers began to apply intelligent algorithms to robotic arms, such as ant colony algorithm, particle swarm algorithm, and genetic algorithm, to name a few. Literature [6] has used ant colony algorithm for robot path planning. All of the above are for path obstacle avoidance planning, but only for path obstacle avoidance, without considering the problem of velocity, and acceleration continuity. Literature [7][12][13][14] has used a genetic algorithm for obstacle avoidance of robot arm using segmented planning, which allows continuity of acceleration as well as velocity, but the segmentation makes too many coefficients to be determined, which makes the computation too complex. To solve the above problems, the article refers to the literature [8] to solve the obstacle avoidance trajectory by changing the coefficients of the six terms of each joint planning, but the design of its fitness function tends to make the algorithm more time-consuming, and at the same time, it is easy to fall into the local optimum and fail to achieve the optimal solution. In this article, we add angular velocity and angular acceleration bounds to the fitness function to optimise the algorithm. The acceleration and velocity of the trajectory are more reasonable and the calculation process is faster.

Manuscript received on 11 October 2023 | Revised Manuscript received on 14 November 2023 | Manuscript Accepted on 15 November 2023 | Manuscript published on 30 November 2023.
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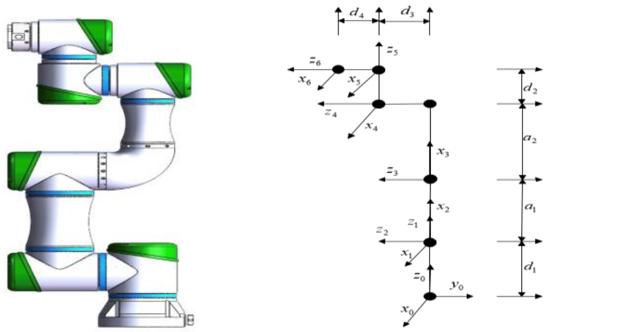
II. COLLISION MODEL

A. Robotic Arm Model

The article studies a six-degree-of-freedom robotic arm, as shown in Fig.1(a) for the 3D model structure of the arm, and Fig.1(b) represents the established simplified linkage coordinate system diagram. Table 1 shows the improved D-H parameter table.



(a)Robot Arm Modeling (b)Coordinate Diagram of Connecting Rod of Manipulator

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Fig. 1 Coordinate Diagram of Joint of Manipulator

Tab.1 DH Parameters of the Manipulator

Connecting rod	a_i /(mm)	α_i /(mm)	d_i /(mm)	θ_i /(°)
1	0	0	144	$\theta_1(0)$
2	0	$\pi/2$	0	$\theta_2(-90)$
3	-264	0	0	$\theta_3(0)$
4	-236	0	106	$\theta_4(-90)$
5	0	$\pi/2$	114	$\theta_5(0)$
6	0	$-\pi/2$	67	$\theta_6(0)$

B. Obstacle Models

Space obstacles are generally irregular geometric shapes, considering that they are too complex, so they need to be simplified, this paper uses a regular body to envelop the obstacle, although this increases the volume of the obstacle, but this greatly simplifies the obstacle domain, thus simplifying the calculation. The regular body has a cylinder, rectangle, sphere and so on. In general, the robot arm uses the cylinder to simplify the envelope. For obstacles you need to look at their nearest regular body. In this paper, the obstacle is simplified by using a rectangular body for the envelope, as shown in Fig.2.

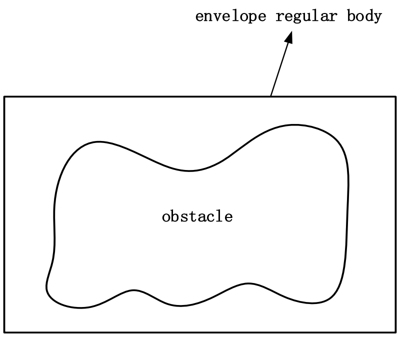

Fig. 2 Irregular Geometric Shape Obstacle Diagram

III. COLLISION DETECTION

This journal uses double-blind review process, which means that both the reviewer (s) and author (s) identities concealed from the reviewers, and vice versa, throughout the review process. All submitted manuscripts are reviewed by three reviewer one from India and rest two from overseas. There should be proper comments of the reviewers for the purpose of acceptance/ rejection.

A. Rectangular Obstacle Space Description

Ellipse and ellipsoid are taken as the basic shapes in reference [9], and different shapes can be represented by varying the parameters in the function expression, and in three dimensions the surface equation can be expressed as：

$$S(x,y,z)=0 \tag{1}$$

The points on this surface which are in accordance with the above equation are those points on the surface where the centre of the obstacle is (x_0,y_0,z_0),The parameters of its geometry. Its spatial surface can be described by the following analytical expression $S(x,y,z)=0$;

$$S(x,y,z)=\left(\left(\frac{x-x_0}{h_1}\right)\right)^{2m}+\left(\left(\frac{y-y_0}{h_2}\right)\right)^{2n}+\left(\left(\frac{z-z_0}{h_3}\right)\right)^{2p}-1 \tag{2}$$

For the description of the rectangular body, it is assumed that the rectangular body has side lengths 2a,2b,2c,centre coordinates (x0,y0,z0) and that its power indices and geometric parameters are satisfied;

$$\begin{cases} h_1=a \\ h_2=b \\ h_3=c \end{cases} \quad \begin{cases} m=4 \\ n=4 \\ p=4 \end{cases} \tag{3}$$

$$S(x,y,z)=\left(\frac{x-x_0}{a}\right)^8+\left(\frac{y-y_0}{b}\right)^8+\left(\frac{z-z_0}{c}\right)^8-1 \tag{4}$$

In the simulation will be simplified into a straight mechanical arm, but because the actual mechanical arm also has a volume, so you need to set the safety distance, the easiest way is to increase the length of the obstacle side, for the rectangle to the centre of the unchanged, but the length of the side of the arm to increase the radius of the mechanical arm twice. As shown in Fig.3.

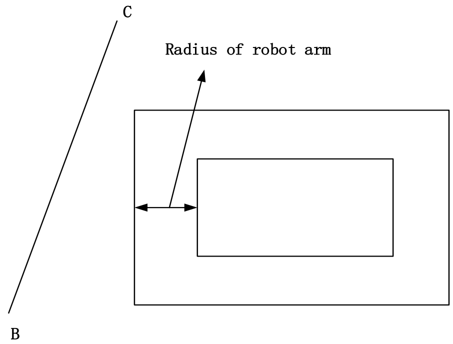

Fig. 3 Position Diagram of Connecting Rod and Obstacle

B. Collision Detection

In Fig.3 b,c are the two articulation points of the robot arm and bc is the robot arm joint. From the robot kinematics it can be concluded that the spatial position of the two points b,c is

$$T_B=T_n Rotz(\theta_1)Trans(0,0,d_1)Tans(a_1,0,0)Rots(\alpha_1) \tag{5}$$

$$T_C=T_n T_B Rotz(\theta_2)Trans(0,0,d_2)Tans(a_2,0,0)Rots(\alpha_2) \tag{6}$$

Equations (5), (6) represent the chi-square articulated transformation matrices of the B,C joint points, so the spatial coordinates of the B and C points are

$$B=\left[x_b,y_b,z_b\right]=\left[T_B(1,4),T_B(2,4),T_B(3,4)\right] \tag{7}$$

$$C=\left[x_c,y_c,z_c\right]=\left[T_C(1,4),T_C(2,4),T_C(3,4)\right] \tag{8}$$

From this we can derive the parametric equation of the space line BC

$$BC:\begin{cases} x=(x_c-x_b)t+x_b \\ y=(y_c-y_b)t+y_b \\ z=(z_c-z_b)t+z_b \end{cases} \tag{9}$$

Substitute the parametric equation for BC into equation (4).

If t has no solution, it means that the arm linkage does not collide.

Retrieval Number: 100.1/ijrte.D79461112423
DOI: 10.35940/ijrte.D7946.1112423
Journal Website: www.ijrte.org

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OPEN ACCESS
International Journal of Recent Technology and Engineering (IJRTE)
ISSN: 2277-3878 (Online), Volume-12 Issue-4, November 2023

If t has a solution, there are two cases, bring t back into the parametric equation of the line BC and find out whether the point is on the line segment BC or not.

(1) If on line segment BC, indicate a collision.

(2) If not in line segment BC, no collision.

Similarly, all the connecting rods on the arm to detect whether a collision occurs, if all the connecting rods do not collide in the operation process, indicating that the arm does not collide. The following fig shows the collision detection flowchart.

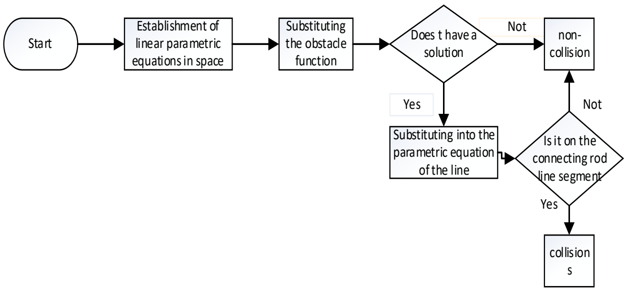

Fig. 4 Flow Chart of Collision Detection

IV. OBSTACLE AVOIDANCE SCHEME BASED ON GENETIC ALGORITHM

A. Fundamentals of Genetic Algorithms

Genetic algorithm is based on the nature of "natural selection" and "survival of the fittest" law of evolution to simulate the biological evolution process random search algorithm. The algorithm has a general direction of application and is simple and easy to understand.The algorithm first randomly generates a number of individuals, each through the fitness function to calculate its fitness value, can be derived from the fitness value of eliminating the lower fitness and retaining the higher fitness. The resulting population is then followed by a new population using crossover, mutation and genetic effects on the individuals. This cycle produces the final result. A sketch of the process is shown in Fig.5.

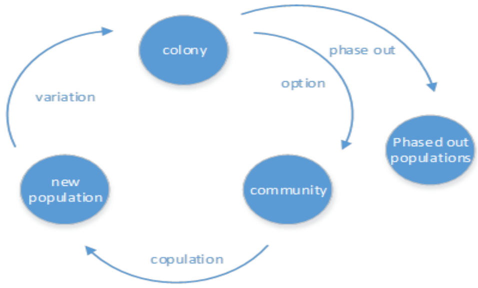

Fig. 5 Schematic Diagram of Genetic Algorithm Process

B. Sixth-Degree Polynomial Programming

Currently, most researchers use fifth-degree polynomials for robot arm trajectory planning. The advantage of fifth degree polynomial planning is the smooth and continuous motion of the robot arm. The disadvantage is that the motion trajectory has uniqueness, this is because there are six boundary conditions in the solution; start and stop angles, start and stop angular velocities, and start and stop accelerations, so the result is unique, which leads to the robotic arm not being able to avoid obstacles. Therefore, the article includes the six times term so that it makes an infinite number of solutions. The optimal trajectory that can avoid obstacles is found by solving the coefficients of the sixth term. This is written as the following equation

$$\theta_i = a_0 + a_1 T + a_2 T^2 + a_3 T^3 + a_4 T^4 + a_5 T^5 + G T^6 \tag{10}$$

where G is the parameter to be determined and θ_i is the i-th joint angle. Let the start time be T_0 and the end time be T_f. Generally, the start time is 0, and then given six boundary conditions, the start and stop angles, start and stop angular velocities, and start and stop angular accelerations are θ_0, θ_f, $\dot{\theta}_0, \dot{\theta}_f, \ddot{\theta}_0, \ddot{\theta}_f$,r, respectively. This results in the following equation

$$\begin{cases} \theta_0 = a_0 \\ \theta_f = a_0 + a_1 T_f + a_2 T_f^2 + a_3 T_f^3 + a_4 T_f^4 + a_5 T_f^5 + G T_f^6 \\ \dot{\theta}_0 = a_1 \\ \dot{\theta}_f = a_1 + 2a_2 T_f + 3a_3 T_f^2 + 4a_4 T_f^3 + 5a_5 T_f^4 + 6G T_f^5 \\ \ddot{\theta}_0 = 2a_2 \\ \ddot{\theta}_f = 2a_2 + 6a_3 T_f + 12a_4 T_f^2 + 20a_5 T_f^3 + 30G T_f^4 \end{cases} \tag{11}$$

The coefficient $a_0 \sim a_5$ can be found when the parameter G is given and the article sets the start and stop velocities as well as the start and stop accelerations to 0. The following equation

$$\begin{cases} a_0 = \theta_0 \\ a_1 = 0 \\ a_2 = 0 \\ a_3 = -(10\theta_0 - 10\theta_f + G T_f^6) / T_f^3 \\ a_4 = (15\theta_0 - 15\theta_f + G T_f^6) / T_f^4 \\ a_5 = -(6\theta_0 - 6\theta_f + G T_f^6) / T_f^5 \end{cases} \tag{12}$$

Equation (12) yields the $a_0 \sim a_5$ coefficients, which can be substituted into equation (10) to obtain its trajectory.

C. Design of the Fitness Function

The adaptation function is designed taking into account collision detection, acceleration, angular velocity limit detection, trajectory length and rotation angle. Equation (13) is the adaptation function

$$F_G = -\frac{f_p f_j f_s}{n_1 f_\theta + n_2 f_c} \tag{13}$$

Where f_p is the collision detection, collision is 0, no collision is 1. f_i is the acceleration limit detection, exceeding the acceleration limit is 0, not exceeding is 1. f_s is the velocity limit detection, exceeding the velocity limit is 0, not exceeding is 1. f_θ is the sum of the joint angular variables. f_c is the sum of the end-effector motions. n_1, n_2 are the weighting coefficients, 1, 0.005 respectively.The inclusion of f_θ and f_c in the above equations is to reduce the movement of its robotic arm while avoiding obstacles, which not only makes the robotic arm energy efficient, but also allows it to complete the operation efficiently. Equations (14), (15) are solved for f_θ and f_c.

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DOI: 10.35940/ijrte.D7946.1112423
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L is solved by using the kinematic positive solution to obtain the final chi-square matrix, which leads to its final spatial coordinate points.

$$f_\theta = \sum_{i=1}^{n}\sum_{j=1}^{6}\left|\theta_{i+1,j} - \theta_{i,j}\right| \quad (14)$$

$$f_c = \sum_{i=1}^{n}\sqrt{(L_{i+1,x} - L_{i,x})^2 + (L_{i+1,y} - L_{i,y})^2 + (L_{i+1,z} - L_{i,z})^2} \quad (15)$$

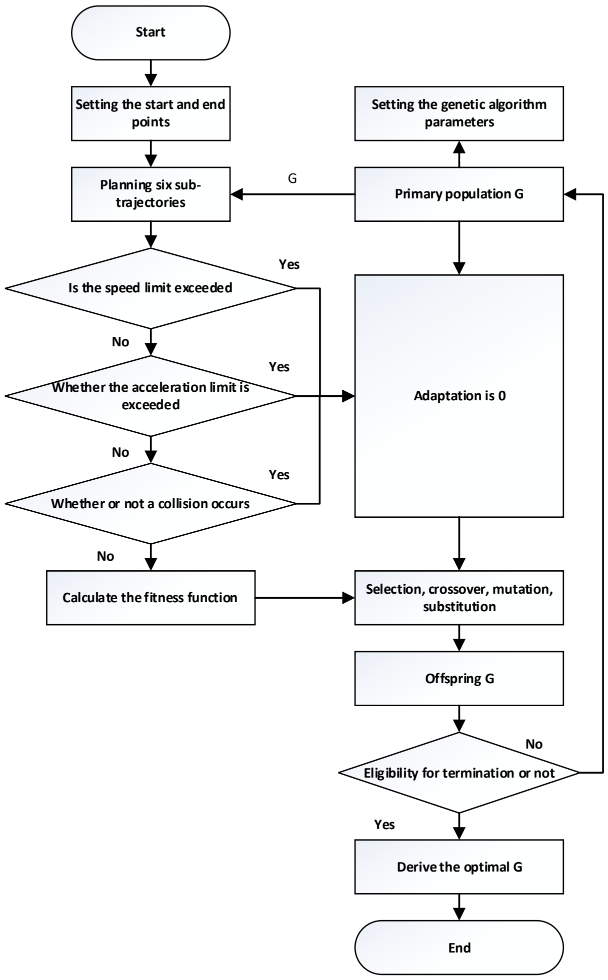

Fig. 6 Flowchart of Obstacle Avoidance Scheme

The addition of q and e to the fitness function has the following advantages; firstly, the fitness is directly 0 if some unreasonable values are calculated, thus skipping the collision detection which requires complex calculation, which can greatly shorten the arithmetic process. Secondly, taking into account the lifetime of the robot arm, a limit is imposed on its speed and acceleration to increase its lifetime. Finally, when the genetic algorithm runs, it may lead to local optimisation, so by adding its constraints, it can jump out of the local optimisation and obtain the global optimisation. Fig.6 shows the flowchart of the entire obstacle avoidance algorithm.

V. EXPERIMENTAL SIMULATION

A. Establishment of Robotic Arms and Obstacles

In this paper, it is jointly established by Robotic Toolbox and Genetic Algorithm Toolbox in MATLAB. Firstly, the robot arm model is set up in MATLAB, and the start joint angle is set to [2*pi/5 pi/4 pi/2 0 0 0], and the end joint angle is set to [-pi/5 pi/4 pi/4 0 pi/4 0]. The obstacle position centre coordinates are [-400 -200 0], side length of [300 200 500] rectangular, respectively, the movement time is 10 seconds, to determine the normal situation of the robot arm will be collided. The Monte Carlo method is used to determine the working space of the robotic arm to determine that the obstacle is within the working space, while the trajectory is planned with a 5th degree polynomial to find that the trajectory passes through the obstacle as shown in Fig.8.

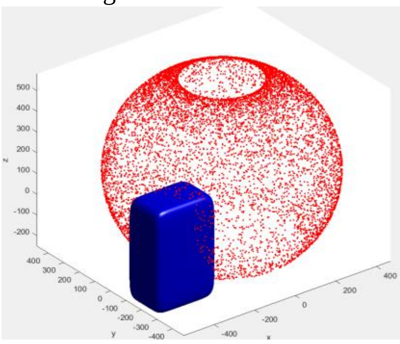

Fig.7 Monte Carlo workspace

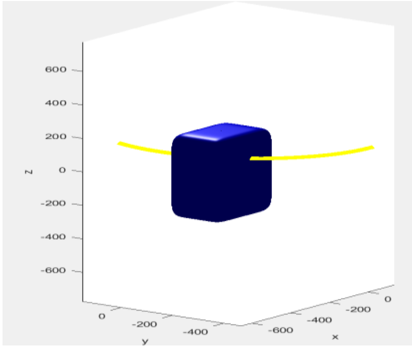

Fig. 8 Relationship between Quintic Polynomial Trajectory and Obstacles

B. Genetic Algorithm for Solving Optimal G and Analyzing the Results

First, the genetic parameters were set, and in order to reduce the amount of computation, the G values were artificially determined to range from [-12 -12 -12 -12 -12 -12 -12] * 1e-5 to [12 12 12 12 12 12 12] * 1e-5, G is a matrix with one row and six columns, because the robot arm has six joints, so the G value should be six.

The angular velocity limit is set to 0.5rad/s, the angular acceleration limit is set to 0.4rad/s2, the number of populations is set to 50, the probability of hybridisation is set to 0.8, the number of elites is set to 3, the termination condition is iterated to 20 generations, and the function is set to the roulette wheel method, The optimal value of G was derived after approximately 10 minutes as [0.2027 0.5488 -0.0171 -0.3314 0.0952 0.2860]*1e-4, with a fitness function of -0.0853, a final movement distance of 1071.7/mm and a joint angle increment of 6.3689/rad.The above iterations were performed 20 times. The average value of its fitness and the optimal value change by iteration is shown in Fig.9, and it can be seen that the optimal value is close to smooth after 7 generations.

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DOI: 10.35940/ijrte.D7946.1112423
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The process of movement of the robot arm and the trajectory of the final movement are shown in Fig.10. From Fig.10 it can be seen that this trajectory can avoid obstacles.

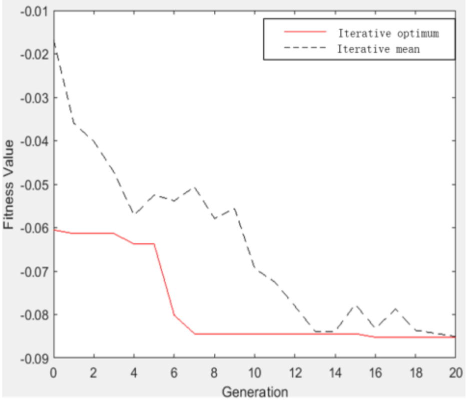


Fig. 9 Iterative Changes of Mean and Optimal Fitness Values

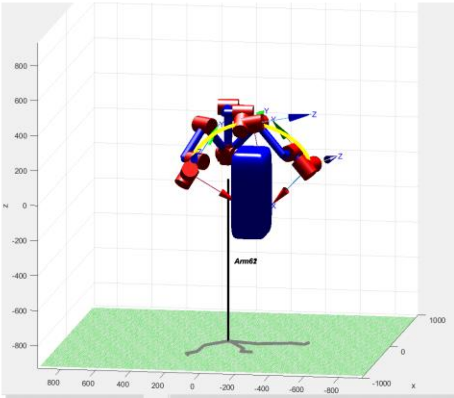
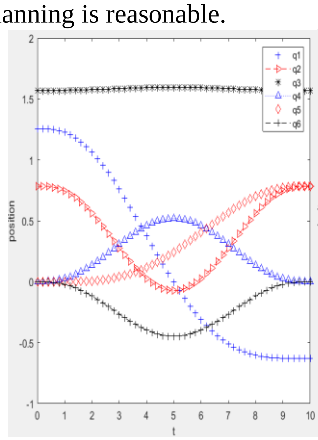


Fig. 10 Motion Process Diagram of the Manipulator

The motion of each joint during the movement is shown in Fig.11, the angular velocity of each joint is shown in Fig.12, the angular acceleration of each joint is shown in Fig.13, and the units of each vertical coordinate in Fig.11, Fig.12, and Fig.13 are rad, rad/s, and rad/s2, respectively, and the units of the horizontal coordinate are all s. From Fig.11, Fig.12, and Fig.13, it is easy to see that the motion of the robot arm is smooth and continuous. At the same time, the limit requirements of the robot arm are not exceeded. The result proves that the robot arm's obstacle avoidance trajectory planning is reasonable.



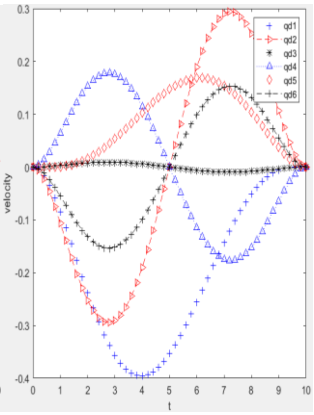


Fig.11 Angles of Each Joint Fig.12 Angular Velocity of Each Joint

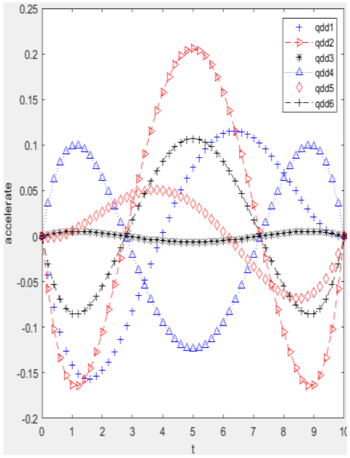


Fig. 13 Angular Acceleration of Each Joint

VI. CONCLUSION

The design of the fitness function in this paper greatly reduces the computation time and can quickly approximate the optimal solution at the beginning of the operation. And the obtained trajectory results are more reasonable, so the life of the robot arm can be strengthened.

The robot arm's obstacle avoidance method uses a genetic algorithm, and the resulting trajectory is not an optimal solution, but a near-optimal solution that meets the requirements. Finding the optimal solution requires many iterations and increases the population. This results in the optimum taking a lot of time to calculate, which is not very meaningful.

The collision detection model is set up so that a variety of regular bodies can be used. The direct function solution method is simple and does not need to consider the spatial geometric relationship between the connecting rod and the obstacle, thus avoiding complicated calculations.

ACKNOWLEDGMENTS

This work was supported by the Key Research and Development Program of Anhui Province (2022i01020015)

DECLARATION STATEMENT

Funding	No, I did not receive.
Conflicts of Interest	No conflicts of interest to the best of our knowledge.
Ethical Approval and Consent to Participate	No, the article does not require ethical approval and consent to participate with evidence.
Availability of Data and Material	Not relevant.
Authors Contributions	All authors have equal participation in this article.

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Masood Usama The master's student at Anhui University of Science and Technology, specializing in the School of Mechanical Engineering, which is deeply immersed in the field of robotics with a specific focus on AI-powered Adaptive Rehabilitation Exoskeletons. His research area encompasses a wide spectrum of robotics, including Robot Design and Control, Kinematics, and Dynamics, particularly in the context of Robot Arms Coordinated Operation and explores the intricate interplay of mechanical design, advanced control systems, with the application of artificial intelligence to create cutting-edge rehabilitation exoskeletons.the student aims to enhance the versatility and adaptability of these systems, ultimately contributing to the advancement of AI-powered robotics in the realm of rehabilitation and beyond.

Xianhua Li is a Professor in Mechanical Engineering at the University of Science and Technology. He obtained a Ph.D. majoring in Mechatronics Engineering at Shanghai University in China. He taught Mechanical Engineering relevant subjects at the School of Mechanical Engineering and School of Artificial Intelligence. His research area is Robotics including Robot Design and Control, Robot Kinematics and Dynamics, Robot Arms Coordinated Operation Control, and Rehabilitation Robot Robot Tip-over, and Slip Avoidance.

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