

Automatic Guided Vehicle Simulation in MATLAB by Using Genetic Algorithm

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1. Introduction

The prodigious advances in robotics in recent times made the use of robots more present in modern society. One important advance that requires special attention is the development of an unmanned aerial vehicle (UAV), which allows an aircraft to fly without having a human crew on board, although the UAVs still need to be controlled by a pilot or a navigator.

Today's UAVs often combine remote control and computerized automation in a manner that built-in control and/or guidance systems perform deeds like speed control and flight-path stabilization. In this sense, existing UAVs are not truly autonomous, mostly because air-vehicle autonomy field is a recently emerging field, and this could be a bottleneck for future UAV development.

It could be said that the ultimate goal in the autonomy technology development is to replace human pilots by altering machines decisions in order to make decisions like humans do. For this purpose, several tools related with artificial intelligence could be employed such as expert systems, neural networks, machine learning and natural language processing (HAYKIN, 2009). Nowadays, the field of autonomy has mostly been following a bottom-up approach, such as hierarchical control systems (SHIM, 2000).

One interesting methodology from the hierarchical control systems approach is the subsumption architecture that decomposes complicated intelligent behavior into many "simple" behavior modules, which are organized into layers. Each layer implements a particular goal and higher layers are increasingly more abstract. The decisions are not taken by a superior layer, but by listening to the information that are triggered by sensory inputs (lowest layer). This methodology allows the use of **reinforcement learning** to acquire behavior with the information that comes with experience.

Inspired by old behaviorist psychology, **reinforcement learning** (RL) concerned with how an agent ought to take actions in an environment, so as to maximize some notion of cumulative reward. Reinforcement learning differs from standard supervised learning in that correct input/output pairs which are never presented (HAYKIN, 2009). Furthermore, there is a focus on an on-line performance, which involves finding a balance between exploration (of uncharted territory) and exploitation (of current knowledge). The reinforcement learning has been applied successfully to various problems, including robot control, elevator scheduling, telecommunications, backgammon and chess (SHIM, 2000).

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Advances in Interdisciplinary Engineering Niraj Kumar, Szalay Tibor, Rahul Sindhvani, Jaesun Lee, Priyank Srivastava, 2021-04-12 This book comprises the select proceedings of the International Conference on Future Learning Aspects of Mechanical Engineering FLAME 2020 This volume focuses on several emerging interdisciplinary areas involving mechanical engineering Some of the topics covered include automobile engineering mechatronics applied mechanics structural mechanics hydraulic mechanics human vibration biomechanics biomedical Instrumentation ergonomics biodynamic modeling nuclear engineering and agriculture engineering The contents of this book will be useful for students researchers as well as professionals interested in interdisciplinary topics of mechanical engineering

Robotic Welding, Intelligence and Automation Tzyh-Jong Tarn, Shan-Ben Chen, Changjiu Zhou, 2007-08-13 Robotic welding systems have been used in different types of manufacturing They can provide several benefits in welding applications The most prominent advantages of robotic welding are precision and productivity Another benefit is that labor costs can be reduced Robotic welding also reduces risk by moving the human welder operator away from hazardous fumes and molten metal close to the welding arc The robotic welding system usually involves measuring and identifying the component to be welded welding it in position controlling the welding parameters and documenting the produced welds However traditional robotic welding systems rely heavily upon human intervention It does not seem that the traditional robotic welding techniques by themselves can cope well with uncertainties in the welding surroundings and conditions e.g variation of weld pool dynamics fluxion solid weld torch and etc On the other hand the advent of intelligent techniques provides us with a powerful tool for solving demanding real world problems with uncertain and unpredictable environments Therefore it is interesting to gather current trends and to provide a high quality forum for engineers and researchers working in the field of intelligent techniques for robotic welding systems This volume brings together a broad range of invited and contributed papers that describe recent progress in this field

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