

# Multi-Input Multi-Output Electric Motor Signal Prediction using Neural Networks

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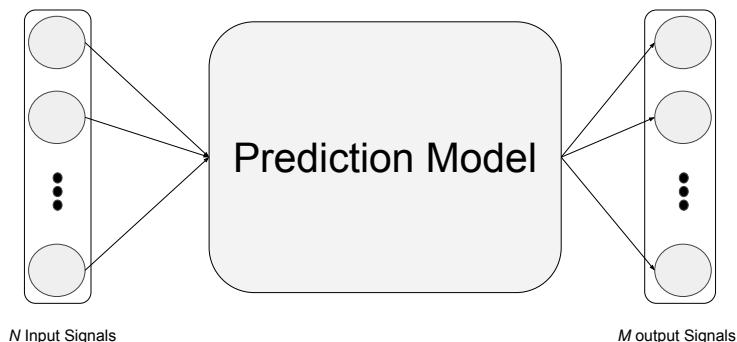
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# What we discussed in the last meeting?

1. Defined the problem
2. Brief introduction of feed-forward and recurrent networks
3. Results on a publicly available time series motor control dataset
4. Error in predicting impulse peaks and scaling problem



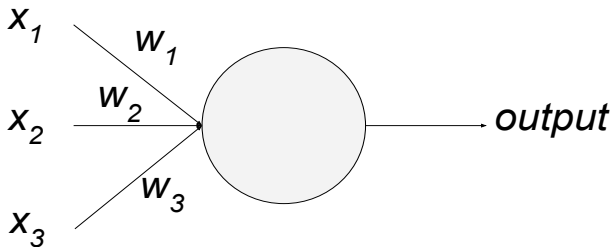
# Dataset

## Description

1. Single experiment
2. 1200 seconds long
3. Simulink dq-frame model is used

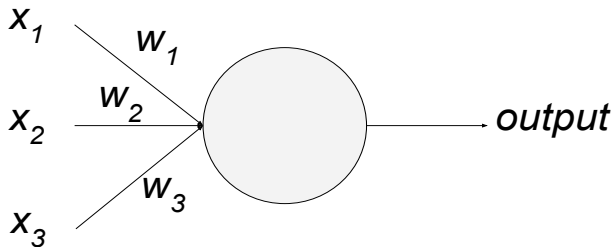
# Dataset

Voltages



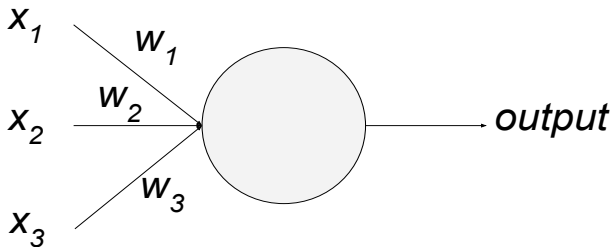
# Dataset

## Stator Pulse



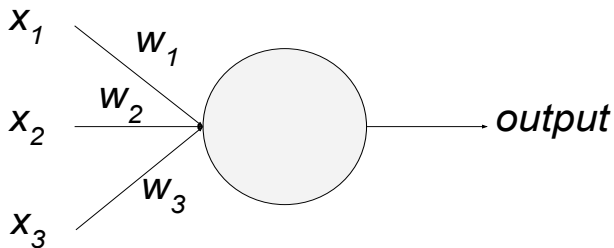
# Dataset

Speed



# Dataset

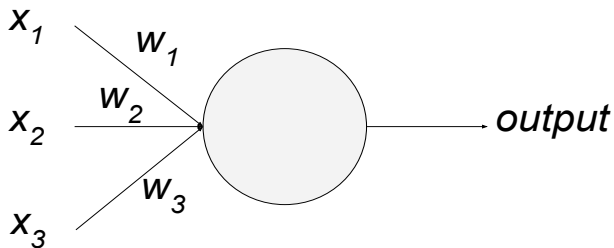
## Currents





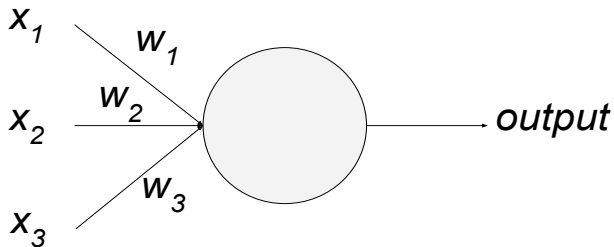
# Dataset

Torque



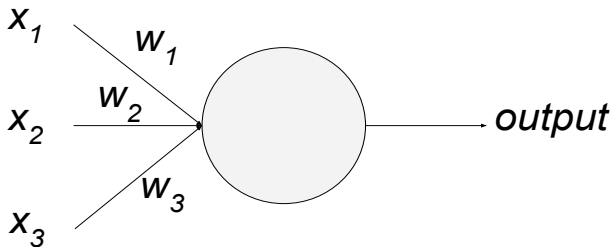
# Dataset

Speed



# Dataset

Voltage2 and Stator Pulse



# Dataset

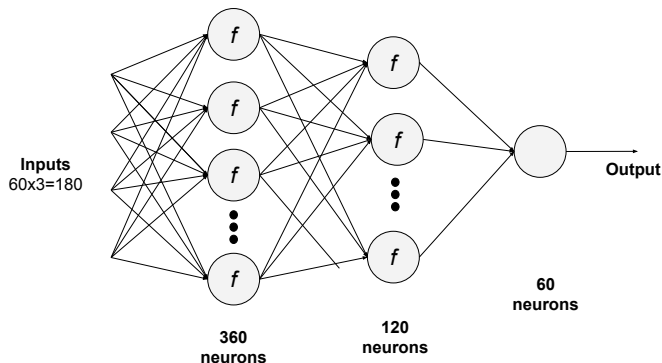
## Train-Test Split

1. Single experiment
2. Biased if splitted like 0-800s and 800-1200s
3. Random sampling
  - 3.1 Take window  $w$  with stride  $s$
  - 3.2 Randomly sample windows
  - 3.3 Train-test cover whole data
  - 3.4 No overlapping b/w train-test

# Experiments

## ANN for signal prediction

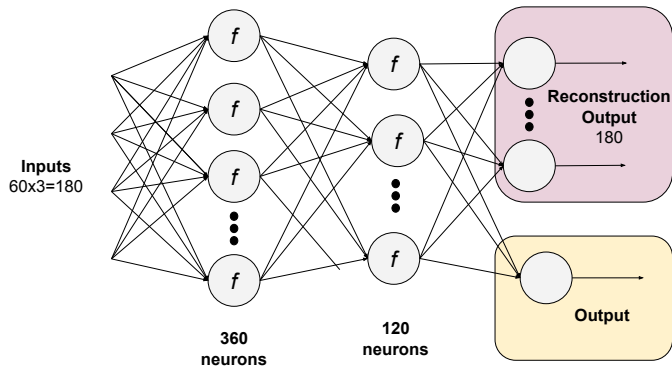
1. Three outputs, three networks.
2. Input:  $w \times 3$  1-D vector, Output: 1 middle value
3. Activation,  $f$ : Leaky Relu



# Experiments

## ANN with auxiliary task

1. Also reconstruct input signal.
2. Three outputs, three networks.
3. Input:  $w \times 3$  2-D vector, Output1: 1, output2:  $w \times 3$  2-D vector
4. Activation,  $f$ : Leaky Relu



# Experiments

## Convolution network

1. CNN and ANN works better then RNN (Miller et al. 2018).
2. Three outputs, three networks.
3. Input:  $w \times 3$  2-D vector, Output1: 1
4. Activation,  $f$ : Leaky Relu

# Results and Conclusions

## Best Model

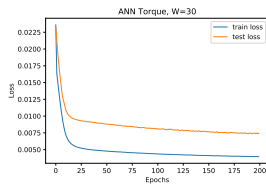
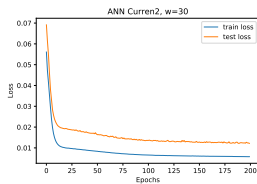
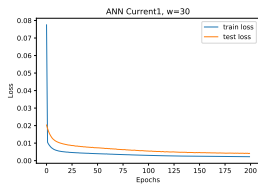
Model	w	Current1	Current2	Torque
ANN	100	0.072	0.197	0.672
	60	0.043	0.105	0.564
	30	<b>0.031</b>	<b>0.091</b>	<b>0.056</b>
LSTM	100	0.146	0.182	0.723
	60	0.136	0.107	0.688
	30	0.045	0.105	0.072
MO-LSTM	60	0.139	0.112	0.691
	30	0.051	0.109	0.081

Table: MSE of different models with different sequence lengths.



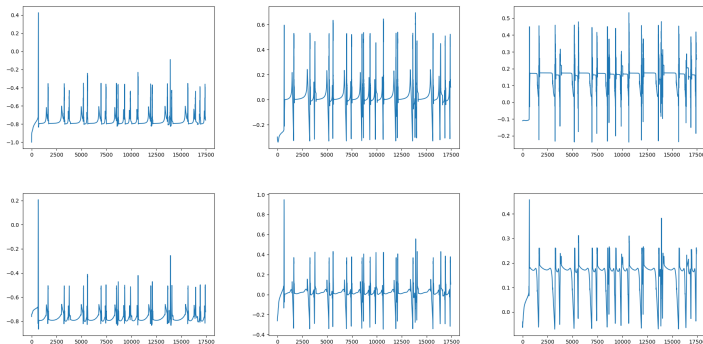
# Results and Conclusions

## Model Convergence



# Results and Conclusions

## Example Outputs



**Figure:** Top row: ground truth, bottom row: predicted signal,  
left to right: current1, current2, and torque

# Results and Conclusions

## Some Answers

1. How to handle continuous signals? **Use tanh**
2. How to handle long sequences? **Find optimal subsequence**
3. Which prediction model to use? **ANN**
4. How to handle multiple outputs? **Independent Models**

Thank you!  
Questions?