A novel robotic handwriting-learning system based on Dynamic Movement Primitives (DMP)

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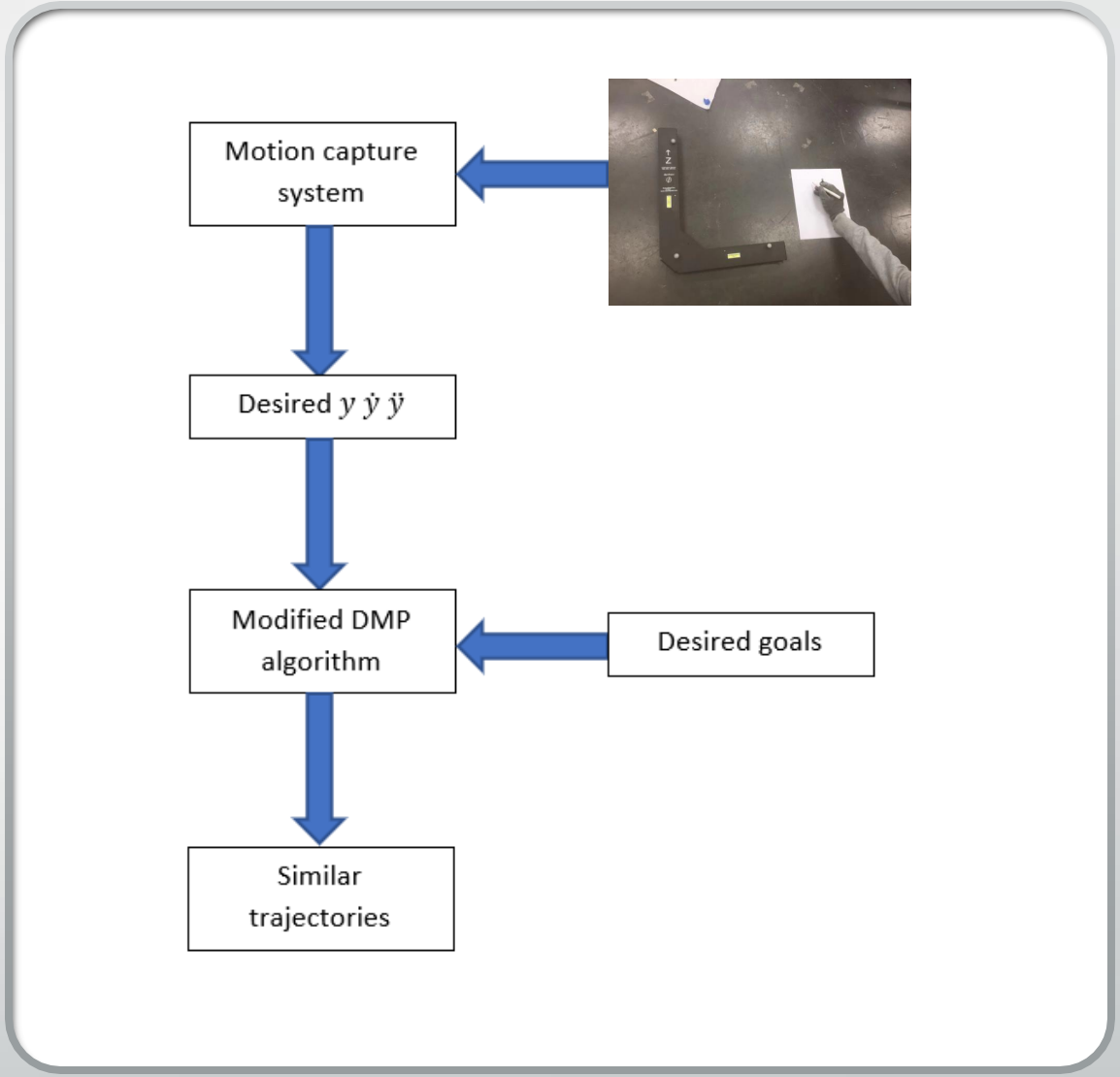
1, Project description

- **Goal:** Design a robot learning system which could capture human's handwriting trajectories(demonstration) and learn from them to create its own handwriting trajectories.
- **Two stages:** Firstly, the robot will precisely imitate human's certain handwriting trajectory. Secondly, the robot will learn the "style" of human's handwriting trajectory and create its own stylistic trajectory based on a standard one.
- **What we have achieved:** We have successfully accomplished the goal in the first stage with our modified DMP algorithm. In this project update, we will analyze our learned trajectories to show the efficiency of our modified DMP algorithm.

1, Project description

- In the first place, we used motion capture hardware system to collect human handwriting data. Then we input the data to our modified DMP algorithm to generate a set of learned points, which are similar to the original ones.



2, DMP Introduction

- Dynamic Movement Primitives (DMP) are a generic framework for motor representation based on nonlinear dynamic systems
- The core idea behind DMP is to perterb a simple linear dynamical system(the left part of equation(1)) with a non-linear component(f) to acquire smooth movements of arbitrary shape.

DMP equations

$$\tau \dot{y} = \alpha_z(\beta_z(g - y) - \tau y) + f \tag{1}$$

$$\tau \dot{x} = -\alpha_x x \tag{2}$$

$$f = \frac{\sum_{i=1}^{N} \psi_i w_i}{\sum_{i=1}^{N} \psi_i} x \tag{3}$$

$$\psi_i = \exp(-h_i(x - c_i)^2) \tag{4}$$

2, DMP Introduction

- To determine the weights of each kernel, we employ Locally Weighted Regression(LWR) to minimize the mean square error(MSE)

$$MSE = \frac{1}{T}\sum_{j=1}^{T}(y_d - y_{learned})^2)$$

- Thus, by using LWR, we can get optimal weights value:

$$w_i = \frac{s^T \psi_i \mathbf{f}}{s^T \psi_i s}$$

$$s = \begin{bmatrix} x_{t_o}(y_g - y_o) \\ \vdots \\ x_{t_N}(y_g - y_o) \end{bmatrix}, \psi_i = \begin{bmatrix} \psi_i(t_o) & \cdots & 0 \\ 0 & \ddots & 0 \\ 0 & \cdots & \psi_i(t_N) \end{bmatrix},$$

$$\mathbf{f} = \begin{bmatrix} \ddot{y}_{t_o} - \alpha_y(\beta_y(y_g - y_{t_o}) - \dot{y}_{t_o}) \\ \vdots \\ \ddot{y}_{t_N} - \alpha_y(\beta_y(y_g - y_{t_N}) - \dot{y}_{t_N}) \end{bmatrix}.$$

3, DMP Modification

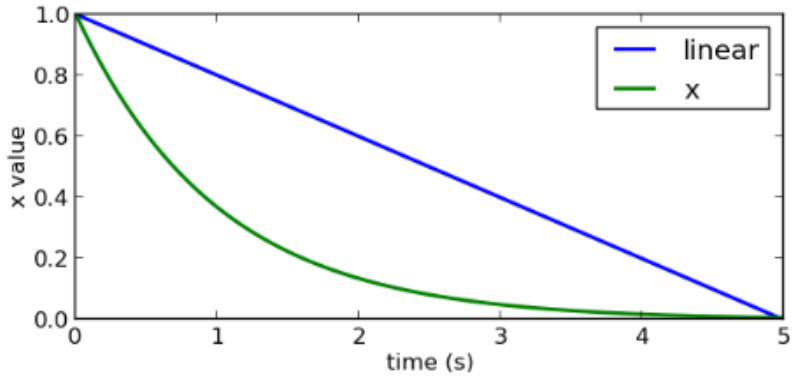
- Due to the complexity of demonstrated handwriting trajectories and the existence of noise, the imitation results were not satisfying by using original DMP algorithm. Thus, we modified the original algorithm to improve its stability and flexibility.

- There are two major modifications:
- The first is to replace the exponential decay system with a linear decay system
- The second is to use a truncated version of Gaussian Kernel Ψi

3, DMP Modification

linear decay system

$$\dot{x} = -\alpha_x x \quad \Longrightarrow \quad \dot{x} = -1/T$$



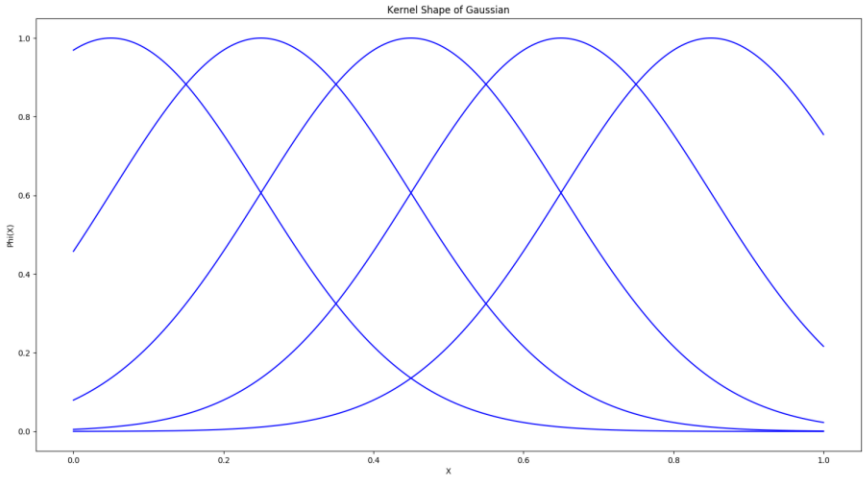
- The advantage of using linear decay system is: The desired magnitude of weights of terminal kernels(as x close to 0) are significantly less. It means that, in linear dacay system, it is more possible to fit curves near the endpoint.

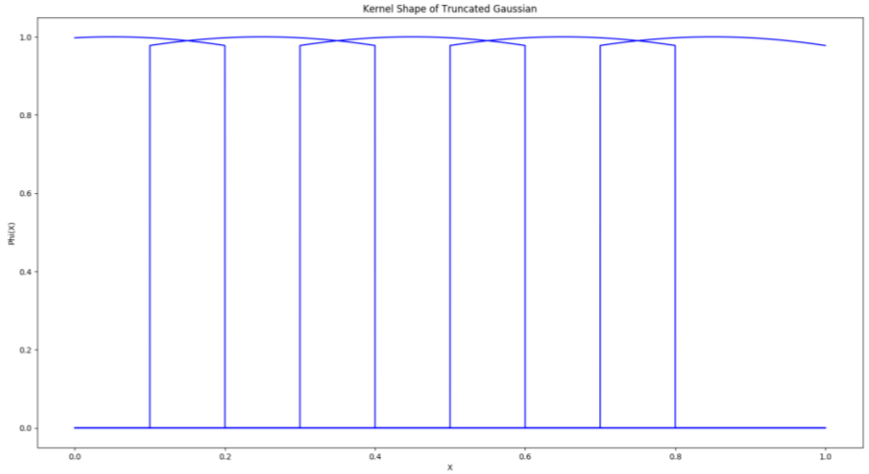
3, DMP Modification

truncated version of Gaussian Kernel Ψi

$$\Psi_i = \exp(-h_i(x - c_i)^2)$$

$$\Psi_i = \begin{cases} \exp(-\frac{h_i}{2}(x - c_i)^2), & \text{if } x - c_i \leq \theta_i \\ 0, & \text{otherwise} \end{cases}$$





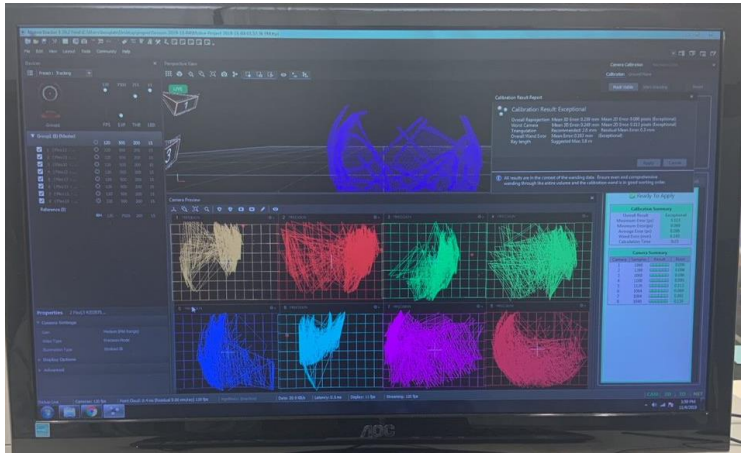
- The advantage of using truncated kernels is that it limits the number of kernels affected by trajectory modification. That's to say, every kernel works more independently, allowing the weights of each kernel more characteristic.

4, Experiment environment

Motion Capture Equipment

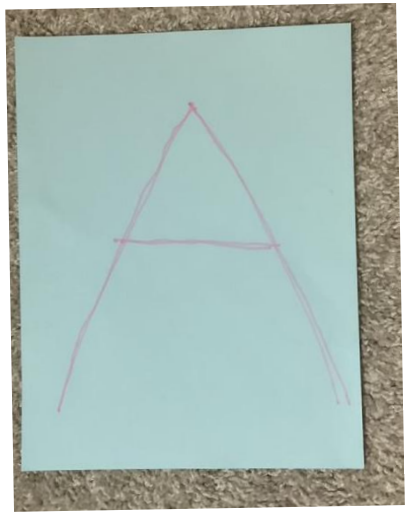
Rigid body as origin

4, Experiment environment



Calibration process (error at lease less than 0.1 cm)

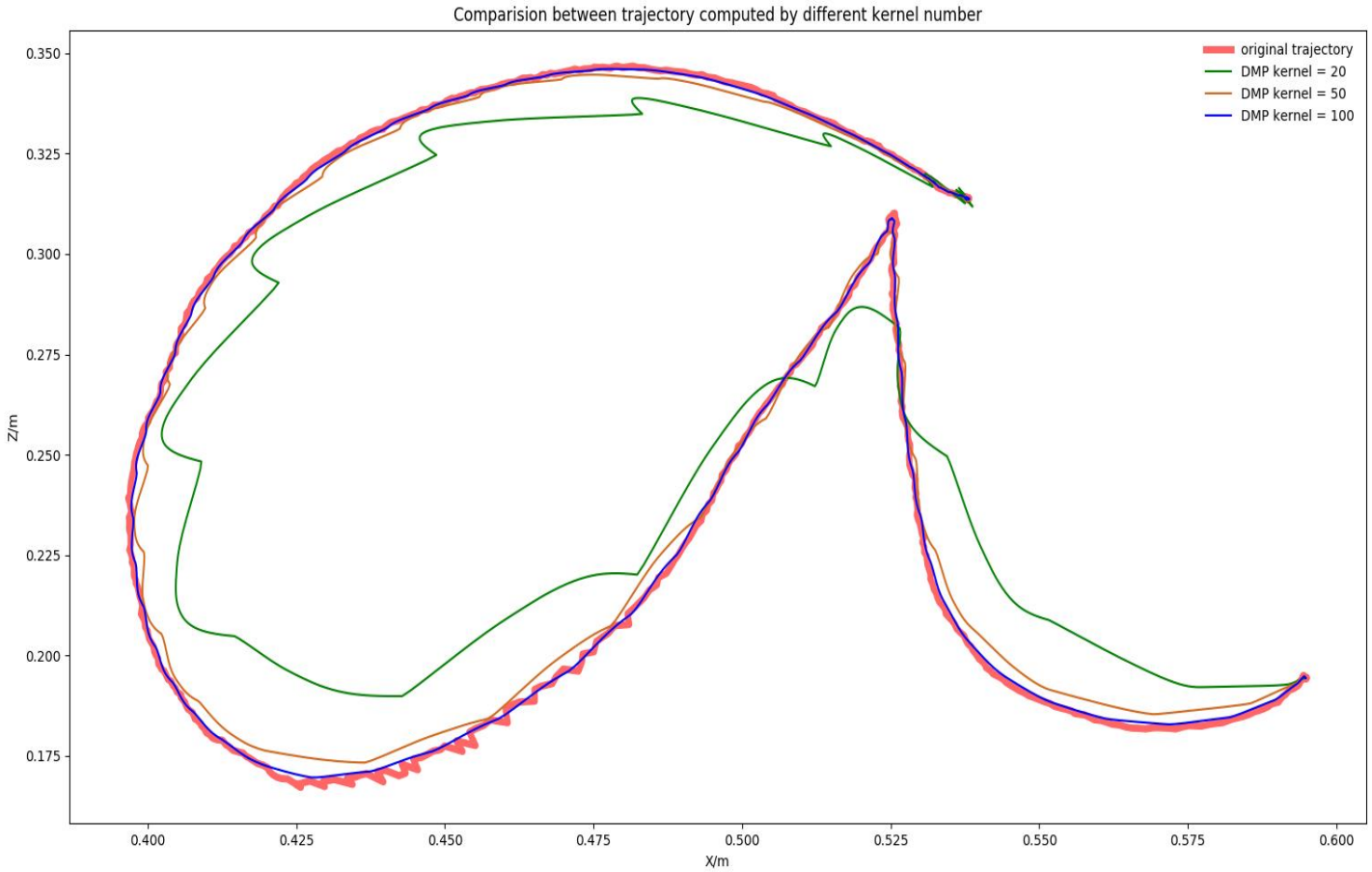
Motion Capture Equipment

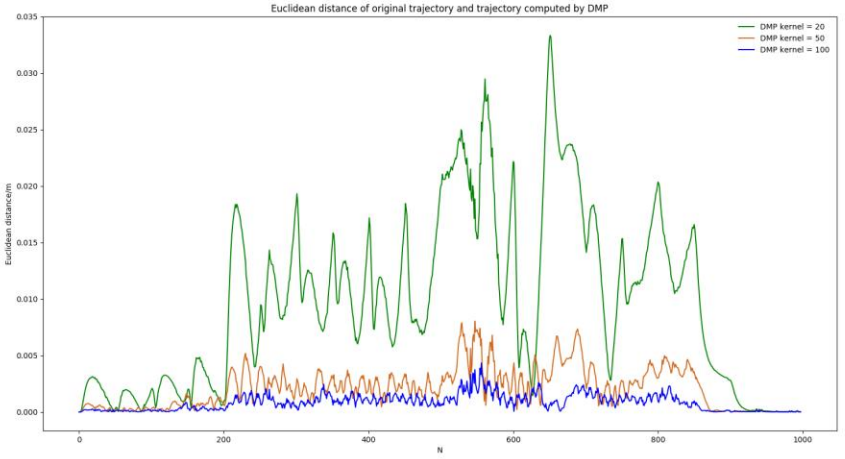


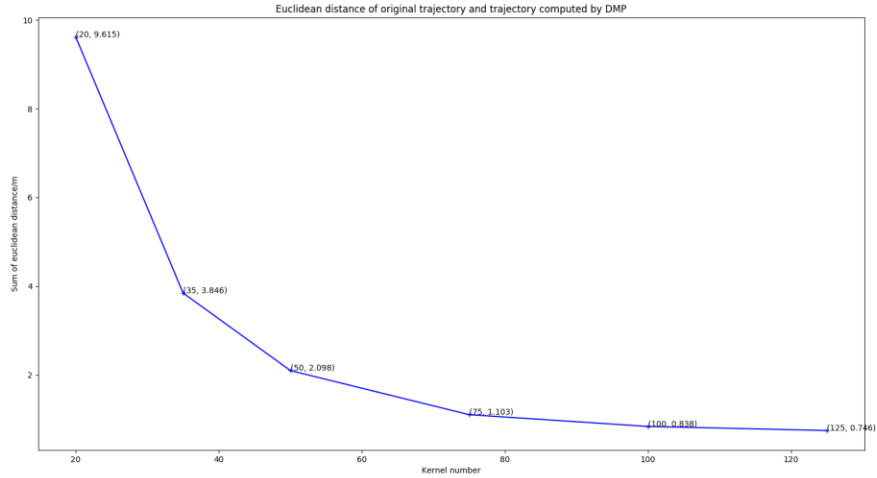
Written Letter on paper

5, Experiment results

Influence of the number of kernel number

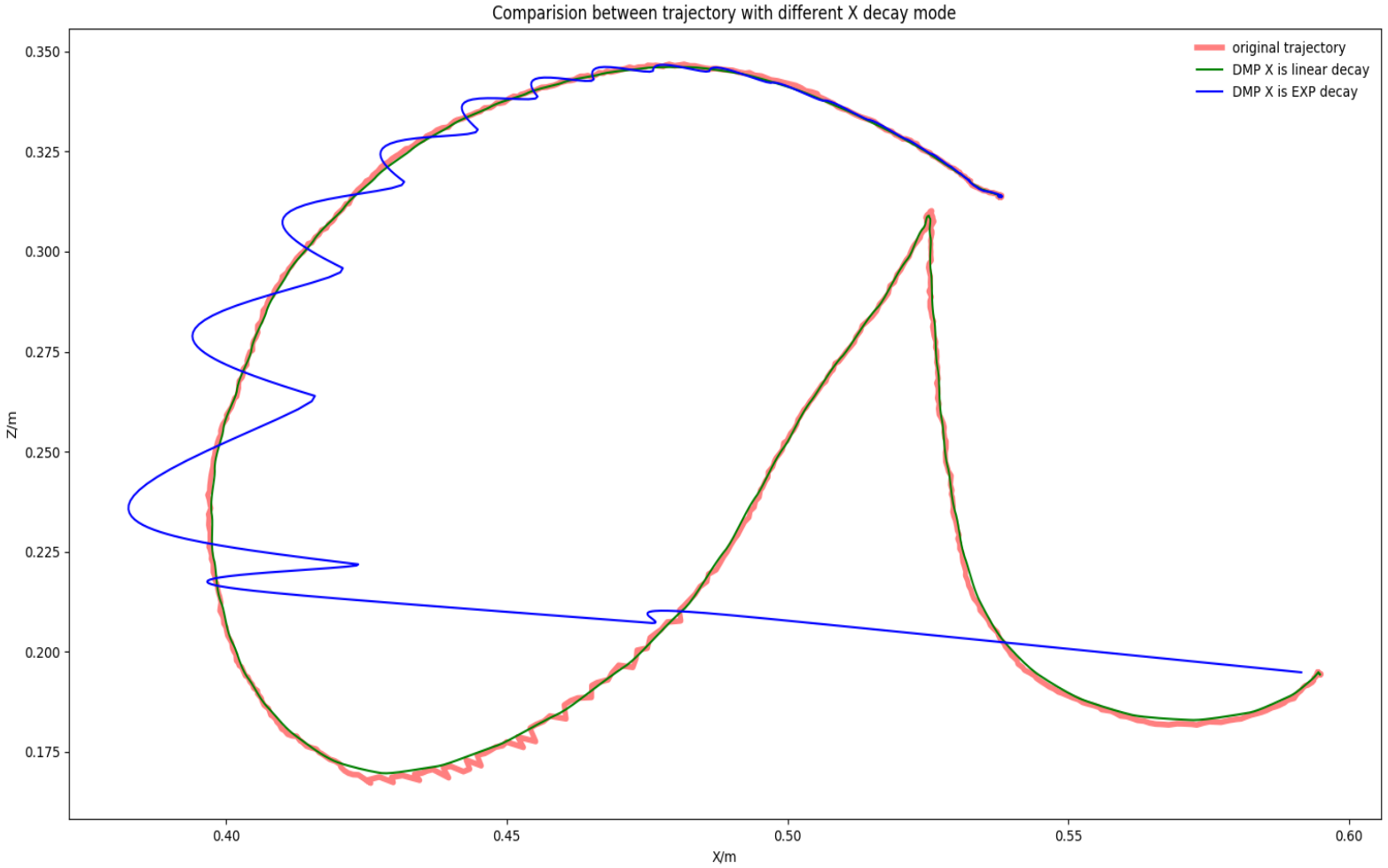


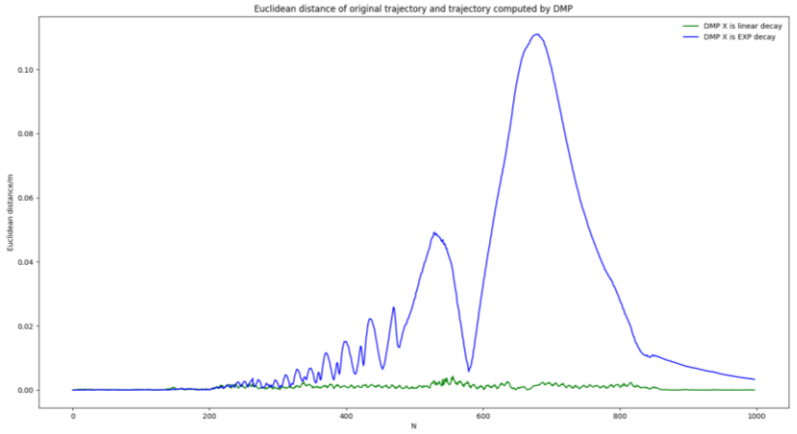




5, Experiment results

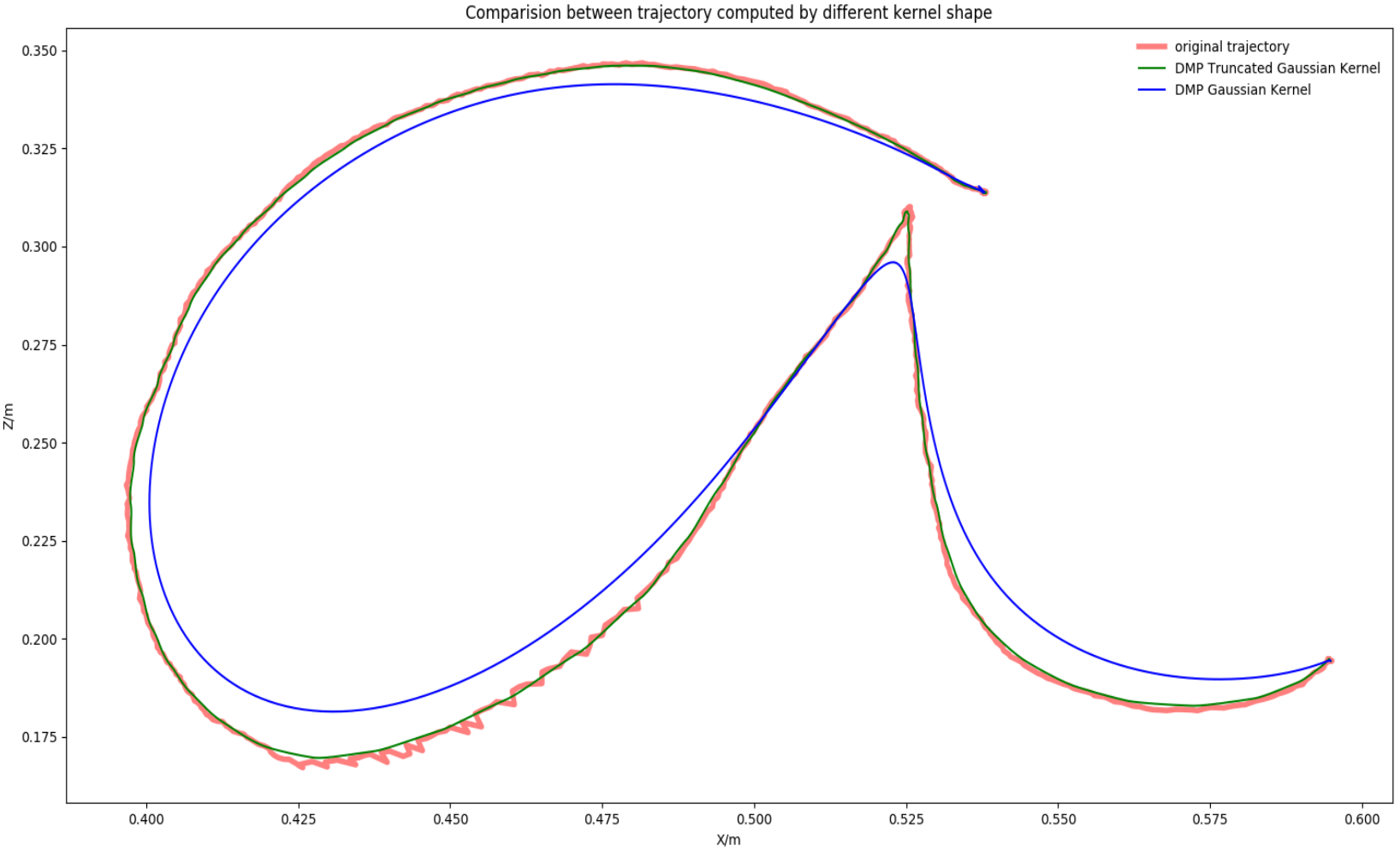
Influence of the number of x decay type

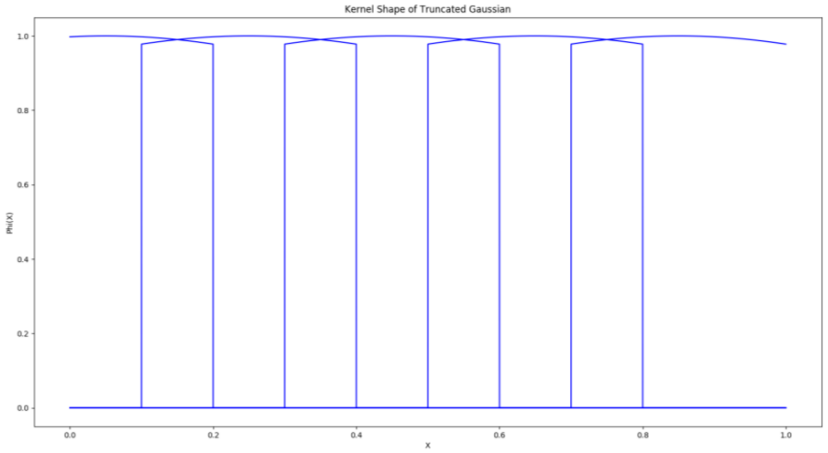


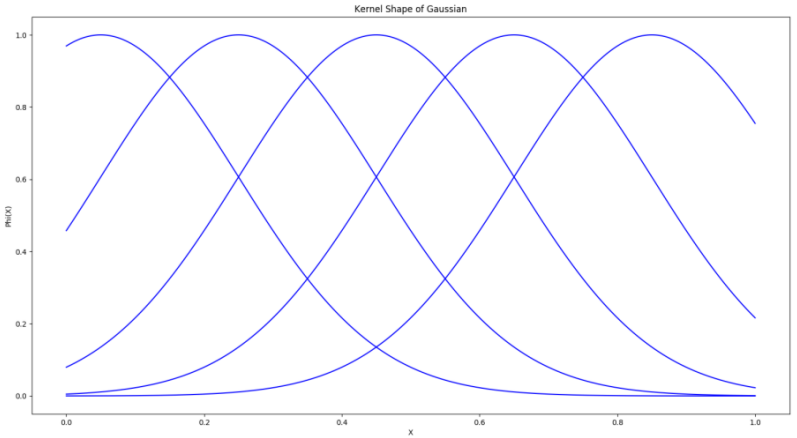


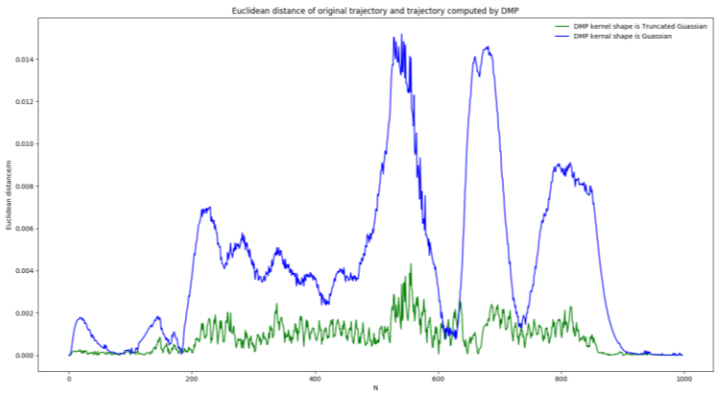
5, Experiment results

Influence of the kernel shape



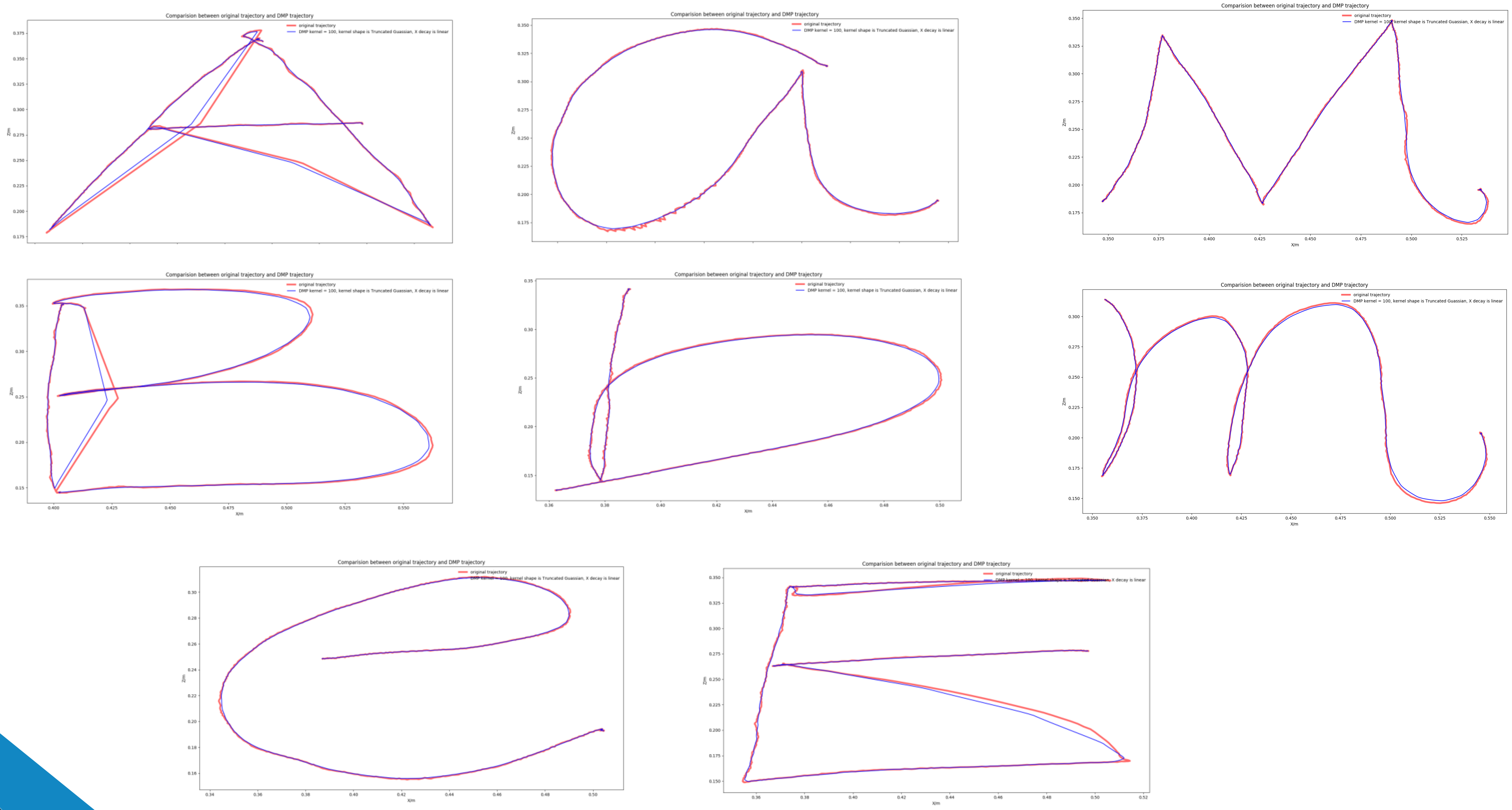




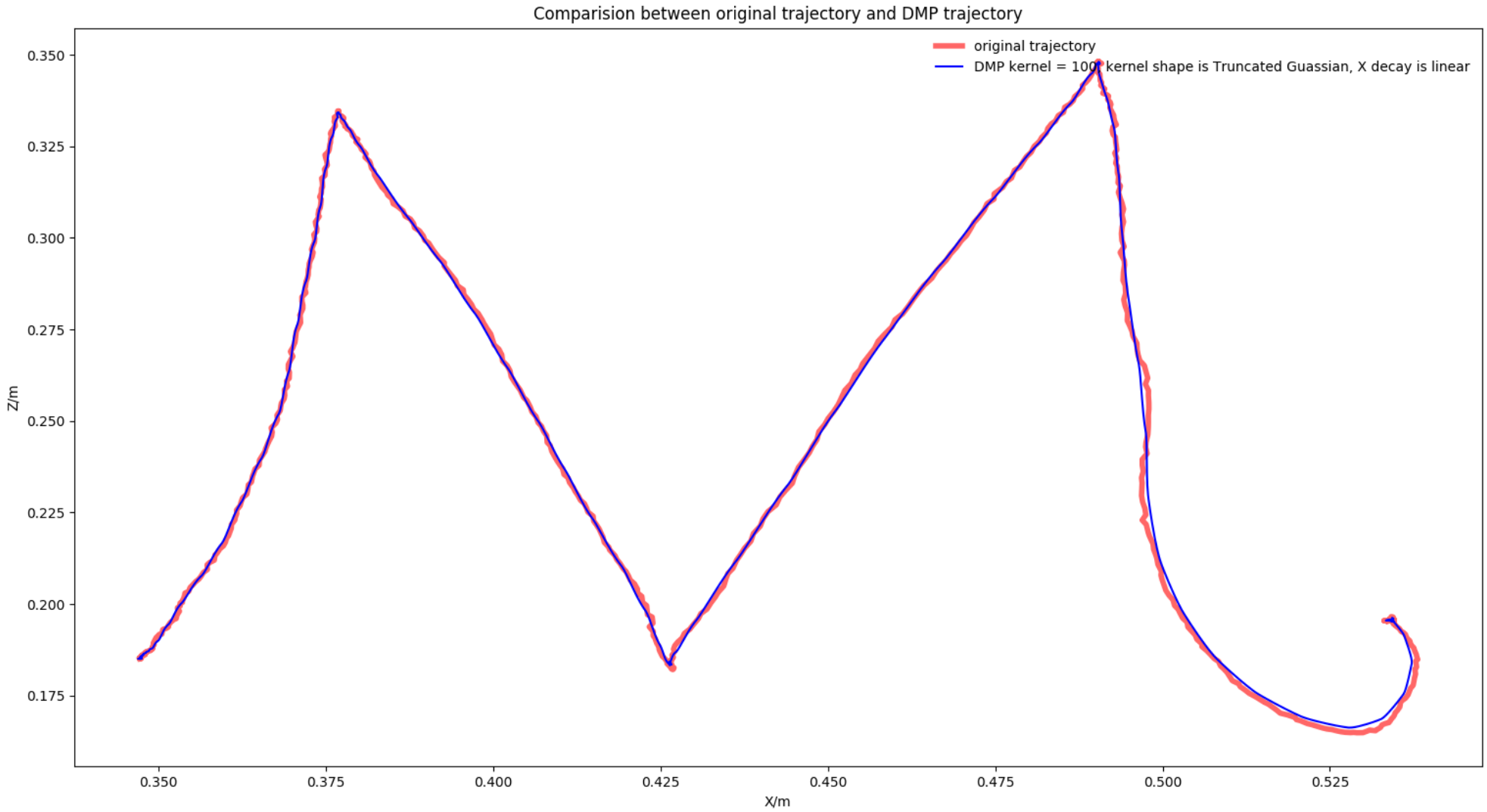


5, Experiment results

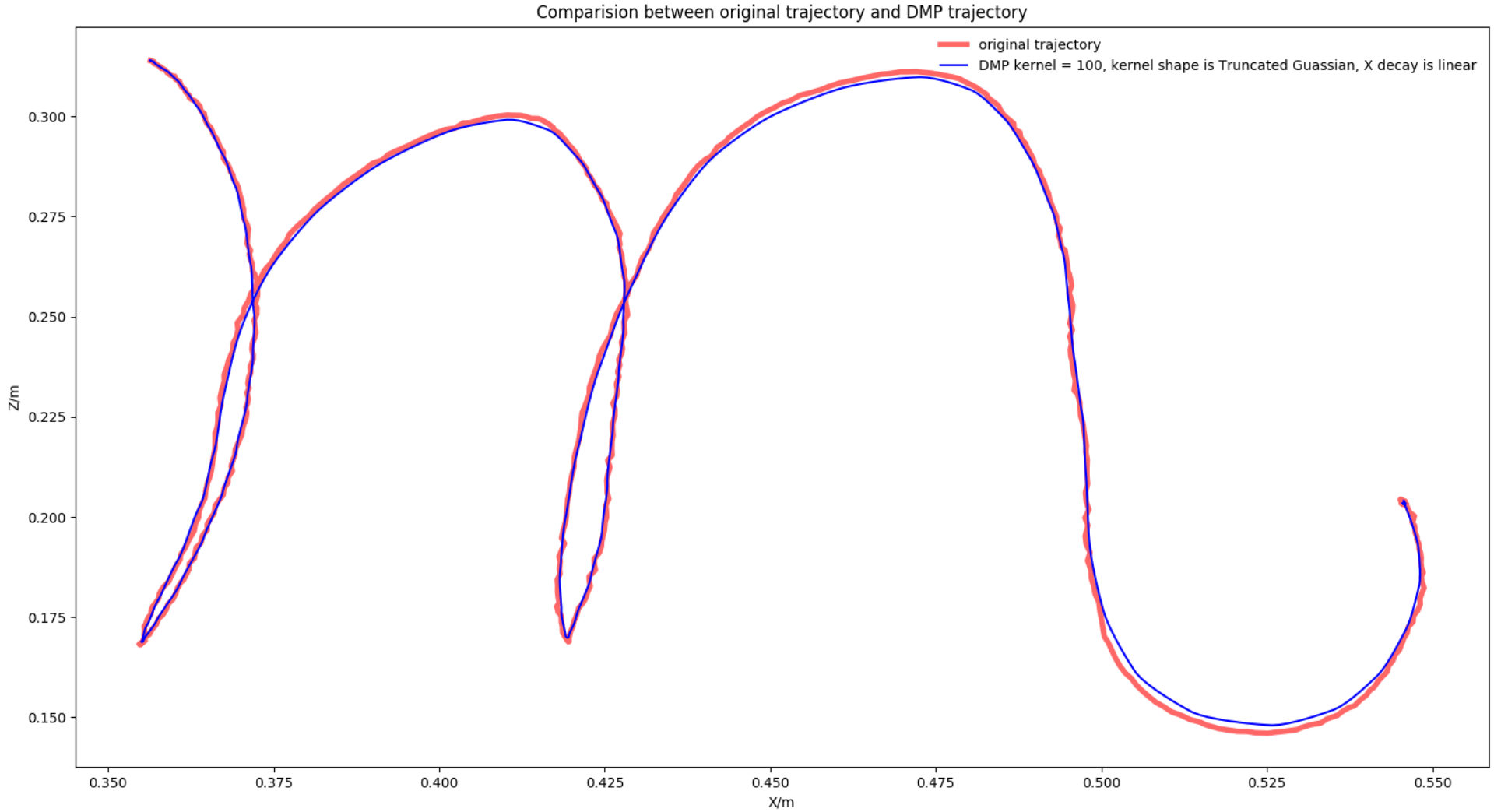
Results of some letter trajectories



5, Experiment results



5, Experiment results



6, Future work

- invite more people to record their writing movement data
- learn the styles of different demonstrators and create stylistic letters based on standard letters
- implement our algorithm on real robot system
- ……

Thank you!