lab02_robot_calib_partial

February 5, 2018

1 Multiple Linear Regression for Robot Calibration

In this lab, we will illustrate the use of multiple linear regression for calibrating robot control. In addition to reviewing the concepts in the multiple linear regression demo, you will see how to use multiple linear regression for time series data – an important concept in dynamical systems such as robotics.

The robot data for the lab is taken generously from the TU Dortmund's Multiple Link Robot Arms Project. As part of the project, they have created an excellent public dataset: MERIt – A Multi-Elastic-Link Robot Identification Dataset that can be used for understanding robot dynamics. The data is from a three link robot:

We will focus on predicting the current draw into one of the joints as a function of the robot motion. Such models are essential in predicting the overall robot power consumption. Several other models could also be used.

1.1 Load and Visualize the Data

First, import the modules we will need.

```
In [1]: import pandas as pd
        import numpy as np
        import matplotlib
        import matplotlib.pyplot as plt
        %matplotlib inline
```

The full MERIt dataset can be obtained from the MERIt site. But, this dataset is large. Included in this repository are two of the ten experiments. Each experiments corresonds to 80 seconds of recorded motion. We will use the following files: * exp1.csv for training * exp2.csv for test

Below, I have supplied the column headers in the `names` array. Use the `pd.read_csv` command to load the data. Use the `index_col` option to specify that column 0 (the one with time) is the *index* column. You can review simple linear regression demo for examples of using the `pd.read_csv` command.

```
In [2]: names =[
            't',                                # Time (secs)
            'q1', 'q2', 'q3',                   # Joint angle   (rads)
            'dq1', 'dq2', 'dq3',                # Joint velocity (rads/sec)
            'I1', 'I2', 'I3',                   # Motor current (A)
```

```
    'eps21', 'eps22', 'eps31', 'eps32',    # Strain gauge measurements ($\mu$m /m )
    'ddq1', 'ddq2', 'ddq3'                 # Joint accelerations (rad/sec^2)
]
# TODO
df = pd.read_csv('exp1.csv', index_col = 0, names = names)
```

Print the first six lines of the pandas dataframe and manually check that they match the first rows of the csv file.

In [3]:
```
# TODO
df.head(6)
```

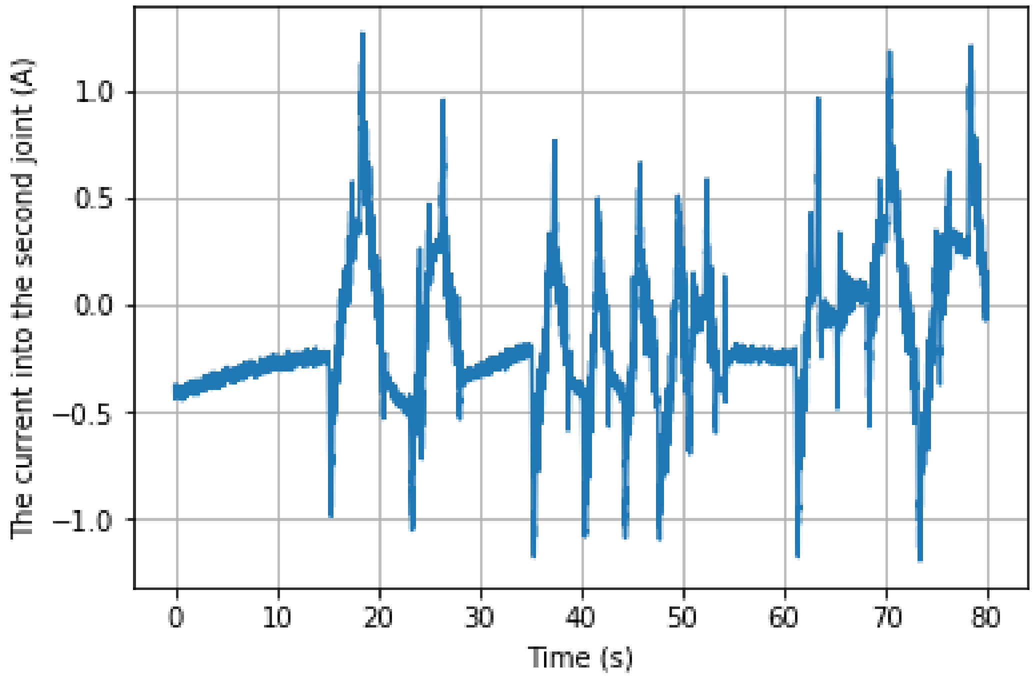
Out[3]:
```
            q1      q2      q3           dq1            dq2           dq3  \
t
0.00 -0.000007  2.4958 -1.1345 -7.882100e-21 -4.940656e-321  3.913100e-29
0.01 -0.000007  2.4958 -1.1345 -2.258200e-21 -4.940656e-321  2.626200e-31
0.02 -0.000007  2.4958 -1.1345 -6.469800e-22 -4.940656e-321  1.762500e-33
0.03 -0.000007  2.4958 -1.1345 -1.853600e-22 -4.940656e-321  1.182800e-35
0.04 -0.000007  2.4958 -1.1345 -5.310600e-23 -4.940656e-321 -5.270900e-03
0.05 -0.000007  2.4958 -1.1345 -1.521500e-23 -4.940656e-321  3.252600e-04

            I1       I2       I3   eps21   eps22   eps31    eps32  \
t
0.00 -0.081623 -0.40812 -0.30609 -269.25 -113.20  3.5918  1.57860
0.01 -0.037411 -0.37241 -0.26698 -270.91 -116.05  1.4585 -1.73980
0.02 -0.066319 -0.40302 -0.31459 -269.25 -112.97  3.5918  0.86753
0.03 -0.068020 -0.43703 -0.28398 -269.97 -114.39  1.6956 -0.08059
0.04 -0.052715 -0.40472 -0.30779 -269.97 -114.15  3.1177  0.86753
0.05 -0.088425 -0.42342 -0.29589 -269.25 -114.15  2.4066 -0.08059

              ddq1           ddq2          ddq3
t
0.00 -9.904900e-19 -6.210306e-319  4.917400e-27
0.01  4.248100e-19 -1.766878e-319 -1.381100e-27
0.02  3.233800e-19 -4.990557e-320 -4.117300e-28
0.03  1.500500e-19 -1.394253e-320 -1.173100e-28
0.04  5.932400e-20 -3.581976e-321 -3.770800e-01
0.05  2.164600e-20 -1.141292e-321  2.930300e-01
```

From the dataframe `df`, extract the time indices into a vector `t` and extract `I2`, the current into the second joint. Place the current in a vector `y` and plot `y` vs. `t`.

In [4]:
```
# TODO
t = df.index.values
y = df.I2.values
plt.plot(t, y)
plt.xlabel('Time (s)')
plt.ylabel('The current into the second joint (A)')
plt.grid()
plt.show()
```



Use all the samples from the experiment 1 dataset to create the training data: * `ytrain`: A vector of all the samples from the `I2` column * `Xtrain`: A matrix of the data with the columns: `['q3','dq2','eps21', 'eps22', 'eps31', 'eps32','ddq2']`

```
In [5]: # TODO
        ytrain = df.I2.values
        Xtrain = df[['q3','dq2','eps21', 'eps22', 'eps31', 'eps32','ddq2']].values
```

1.2 Fit a Linear Model

Use the `sklearn.linear_model` module to create a `LinearRegression` class `regr`.

```
In [6]: from sklearn import linear_model

        # Create linear regression object
        # TODO
        regr = linear_model.LinearRegression()
```

Train the model on the training data using the `regr.fit(...)` method.

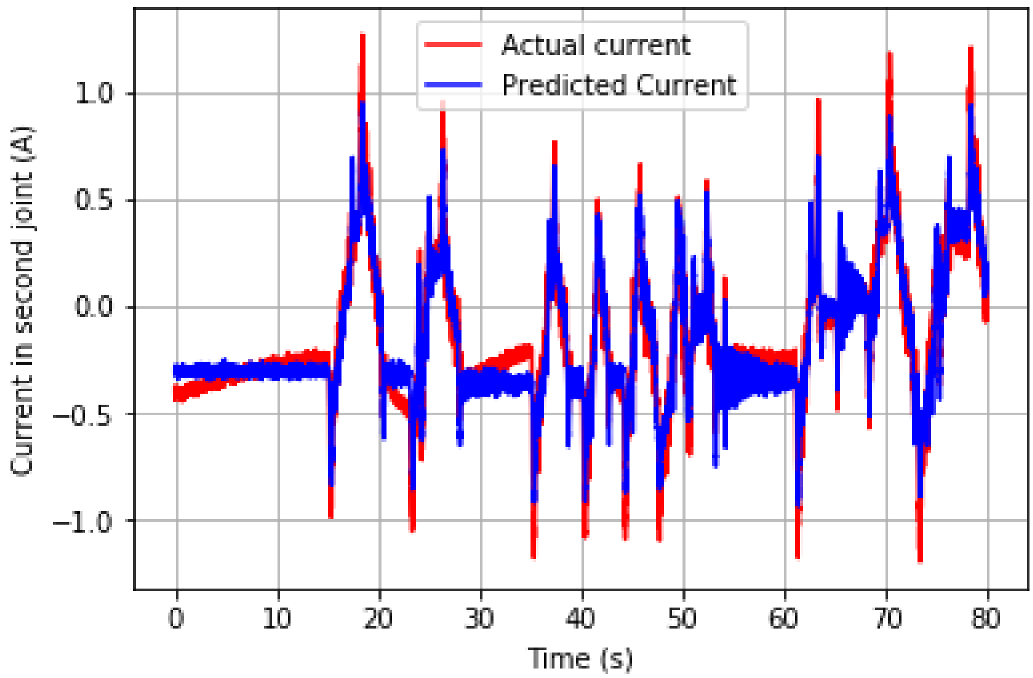
```
In [7]: # TODO
        regr.fit(Xtrain, ytrain)
```

```
/usr/local/lib/python3.6/site-packages/scipy/linalg/basic.py:1226: RuntimeWarning: internal gel
  warnings.warn(mesg, RuntimeWarning)
```

Out[7]: LinearRegression(copy_X=True, fit_intercept=True, n_jobs=1, normalize=False)

Plot the predicted and actual current I2 over time on the same plot. Create a legend for the plot.

In [8]:
```
# TODO
ytrain_pred = regr.predict(Xtrain)
plt.plot(t, ytrain, 'r', label = 'Actual current')
plt.plot(t, ytrain_pred, 'b', label = 'Predicted Current')
plt.xlabel('Time (s)')
plt.ylabel('Current in second joint (A)')
plt.legend()
plt.grid()
plt.show()
```



Measure the normalized RSS given by

$$\frac{RSS}{ns_y^2}.$$

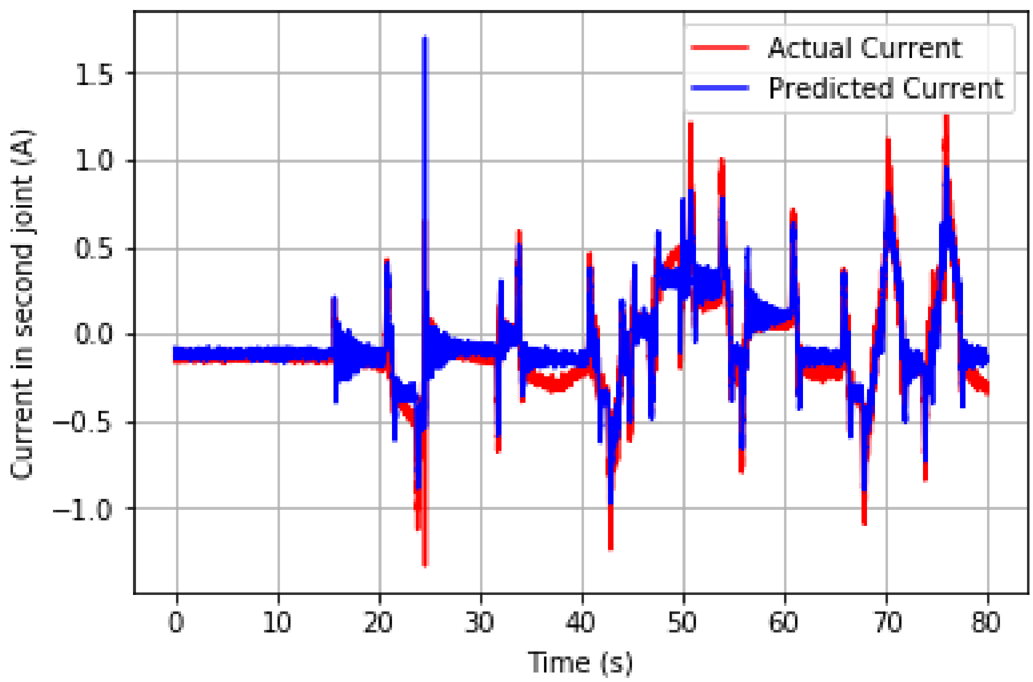
In [9]:
```
# TODO
RSS_train = np.mean((ytrain_pred - ytrain) ** 2) / (np.std(ytrain) ** 2)
print('RSS_train is %0.4f' % RSS_train)
```

```
RSS_train is 0.0966
```

1.3 Measure the Fit on an Indepdent Dataset

Load the data in `exp2.csv`. Compute the regression predicted values on this data and plot the predicted and actual values over time.

```
In [10]: # TODO
         df2 = pd.read_csv('exp2.csv', index_col = 0, names = names)
         ytest = df2['I2'].values
         Xtest = df2[['q2','dq2','eps21', 'eps22', 'eps31', 'eps32','ddq2']].values
         ytest_pred = regr.predict(Xtest)
         plt.plot(t, ytest, 'r', label = 'Actual Current')
         plt.plot(t, ytest_pred, 'b', label = 'Predicted Current')
         plt.xlabel('Time (s)')
         plt.ylabel('Current in second joint (A)')
         plt.legend()
         plt.grid()
         plt.show()
```



Measure the normalized RSS on the test data. Is it substantially higher than the training data?

```
In [11]: # TODO
         RSS_test = np.mean((ytest_pred - ytest) ** 2) / (np.std(ytest) ** 2)
         print('RSS_test is %0.4f' % RSS_test)
         print('The normalized RSS on the test data is substantially higher than that on the t
```

```
RSS_test is 0.1270
The normalized RSS on the test data is substantially higher than that on the training data.
```