
Conclusions

The presented method of determining the critical points is based on the graph theory and some features of the adjacency matrix, which represents graphs. Searching for critical points in computer networks, as it follows from the above researches is characterized with a large complexity and requires applying of a great computational performance. However, the main advantage of this method is a fact that it uses homogenous structures, and the computations itself are of the same type. Presented experiments were implemented and realized on the multiprocessor cluster and the results of these experiments are presented in the above table. Analyzing these experimental results, the conclusion may be drawn independently.

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Authors' Information

Krivoi Sergey – Glushkov Institute of Cybernetics NAS of Ukraine, Ukraine, Kiev, 03187, 40 Glushkova Street, Institute of Cybernetics, e-mail: krivoi@i.com.ua

Hajder Miroslaw – Technical University of Rzeszow, Rzeszow, Poland, e-mail: mhajder@prz.rzeszow.pl

Dymora Pawel – Technical University of Rzeszow, Rzeszow, Poland, e-mail: pdymora@prz.rzeszow.pl

Mazurek Miroslaw – Technical University of Rzeszow, Rzeszow, Poland, e-mail: mmazurek@prz.rzeszow.pl

ROBOT CONTROL USING INDUCTIVE, DEDUCTIVE AND CASE BASED REASONING

Agris Nikitenko

Abstract: *The paper deals with a problem of intelligent system's design for complex environments. There is discussed a possibility to integrate several technologies into one basic structure that could form a kernel of an autonomous intelligent robotic system. One alternative structure is proposed in order to form a basis of an intelligent system that would be able to operate in complex environments.*

The proposed structure is very flexible because of features that allow adapting via learning and adjustment of the used knowledge. Therefore, the proposed structure may be used in environments with stochastic features such as hardly predictable events or elements. The basic elements of the proposed structure have found their implementation in software system and experimental robotic system. The software system as well as the robotic system has been used for experimentation in order to validate the proposed structure - its functionality, flexibility

and reliability. Both of them are presented in the paper. The basic features of each system are presented as well. The most important results of experiments are outlined and discussed at the end of the paper. Some possible directions of further research are also sketched at the end of the paper.

Keywords: Artificial intelligence, Inductive reasoning, Deductive reasoning, Case based reasoning, Machine learning, Learning algorithms.

Introduction

During a short period of time (lasting only several decades) there have been developed a lot of different technologies and approaches to solve various types of problems existing in the field of artificial intelligence. A complexity of those tasks that can be performed by intelligent systems is growing from year to year. Therefore, the range of application of artificial intelligence (AI) technologies has been significantly widened. One of the challenging tasks that is always hard to accomplish is building an autonomous intelligent robotic system, because it includes design of software, hardware and mechanics as well. The task is even more challenging if an operation environment is complex and has some stochastic features or entities with stochastic behavior.

Before trying to build a structure of an autonomous intelligent robotic system, it is necessary to define the environment in which the system should be able to operate. A basis of such a definition can be found in the assumption that every object can be described as a system [Lit.1] Obviously, a complex environment can be described as a complex system. There are several very basic features that define a complex system [Lit. 2]:

- uniqueness – usually complex systems are unique or number of similar systems is unweighted.
- hardly predictable – complex systems are very hard to predict. It means that it is hard to calculate the next state of a complex system if the previous states are known. The hard predictability may be related of the mentioned stochastic elements or features of the environment.
- an ability to maintain some progress resisting against some outer influence (including influence of the intelligent system).

Of course, any complex system has every general feature such as a set of elements, a set of relations or links etc... [Lit. 3]

Obviously, if the system operates autonomously in a complex environment, it has to form some model of the environment. It is not always possible to build a complete model of the environment for different reasons. That may be caused by a huge space of possible states of the environment (or even infinite), expanses or other reasons. It means that an intelligent system will use only an incomplete model of the environment during operation and be able to achieve its goals.

The structure presented in the paper exploits an adaptation and uncertain reasoning technique as general methods to deal with an incompleteness of the system's model of its environment.

Basic Feature of the Intelligent System

In this section the basic features of the proposed structure are outlined and explained according to the previous research activities [Lit.4].

Summarizing the basic features of the proposed structure are as following:

- An ability to generate a new knowledge from the already existing in the system's knowledge base. This ability can be achieved by means of deductive reasoning. In order to increase the efficiency a case based reasoning may be used [Lit.6] This feature, obviously, includes also an ability to reason logically. The proposed structure does not state the kind of deductive reasoning that should be used. The only rule is that the selected deductive reasoning method has to address demands of a particular task. As it is described above, complex environments may be very dynamic and even with stochastic features. Therefore, some uncertain reasoning techniques may be the most suitable for complex environments. The described below experimental systems also have uncertain reasoning techniques implemented as a deductive reasoning module.
- An ability to learn. As it is assumed above in complex environments the intelligent system eventually will not have a complete model of the environment. Therefore, the environment will be hardly predictable. Also complex environments are dynamic - in other words the system will face with new situations very often. Obviously, some mechanisms of adaptation should be utilized. From point of view of intelligence, an

adaptation includes the following main capabilities: a capability of acquiring new knowledge and adjustment of the existing knowledge. The inductive reasoning module refers to capability of acquiring new knowledge or learning, in other words. This feature may be implemented by means of inductive reasoning. During an operation, the intelligent system collects a set of facts through sensing the environment that forms input for learning.

- An ability to reason associatively. This feature is necessary due to a huge set of possible different situations that the intelligent system may face with. For example, there may be two different situations that can be described by n parameters (n is big enough number) where only k parameters are different (k is small enough number). Obviously, these situations may be assumed as similar. Therefore an associative reasoning is used – to reason about objects or situations that are observed for the first time by the intelligent system similarly to reasoning about known situations and using knowledge about the known situations and object. The associative reasoning is realized through using associative links among similar objects and situations. An issue about which objects and situations should be linked is conditioned by particular tasks or goals of the system's designer.
- An ability to sense an environment. This feature is essential for any intelligent system that is built to be more or less autonomous. This feature also includes an ability to recognize objects / situations that the system has faced with as well as an ability to obtain data about new objects. All sensed data is structured in frames (see below). During the frame formation process the sensed environment's state is combined with system's inner state thereby allowing the system to reason about system itself as well as relation between system's inner state and sensed environment's state. Also, the sensed system's and environment's states are used to realize a feedback in order to adjust system's knowledge. Thus, the system's flexibility is increased.
- An ability to act. This feature is essential for any intelligent system that is designed to do something. If the system (autonomous) is unable to act, it will not be able to achieve its goals. Obviously, the system has to act in order to achieve its goals as well as to obtain the feedback information for readjusting its knowledge or to learn new knowledge. The way of acting and the purpose of acting vary depending of goals of the system's designer or user.

The listed above features form the basis for an intelligent system that operates in sophisticated environment. According to the features of complex systems that are listed above, any of them may be implemented, as it is needed for a particular task. In other words, the implementation methods and approaches are dependent of the purposes of the system itself.

Nevertheless the main question is how to bind all of the listed above features in one whole - one intelligent system.

Obviously, there is a necessity for some kind of integration. There are many good examples of different kinds of integration. For example so called soft computing which combines fuzzy logic with artificial neuron nets [Lit.6] or Case based reasoning combined with deductive reasoning [Lit.7].

In order to adjust an intelligent system for some particular tasks different structures may be used [Lit 14]. This paper presents one of the alternative structures that may be used in order to implement all of the listed above features and may form a kernel of autonomous intelligent system.

The proposed structure is based on intercommunicating architecture. In other words, the integrated modules are independent, self-contained, intelligent processing modules that exchange information and perform separate functions to generate solutions [Lit. 14].

Structure of the Intelligent System

According to the list of very basic features there can be outlined the basic modules that correspond to the related reasoning techniques:

As it is outlined in the figure 1, there are four basic modules that form system's kernel. Each of the modules has the following basic functions

- *Deductive reasoning module*. This module performs deductive reasoning using *if..then* style rules. In order to implement adaptation functionality, this module may exploit some of uncertain reasoning techniques. In the proposed structure the main purpose of this module is to predict future states of the environment as well as the inner state of the system. During the reasoning process *if..then* rules are used in combination with input data obtained from system's sensors. The proposed structure itself does not state what kind of deductive reasoning method should be used. It depends of particular goals of the system's designer. In both practical

implementations a forward chaining certainty factor based reasoning had been used [Lit.17]. If a task requires fuzzy reasoning or other reasoning technique may be used as well.

- *Inductive reasoning module.* This module performs an inductive reasoning or in other words – inductive learning. It learns new rules and adds them to the rule base. Also, the incoming data from system's sensors is used. Again, the proposed structure does not state what kind of inductive learning technique is used. The only limitation is a requirement to produce rules that could be used by the deductive reasoning module. For example, if the fuzzy reasoning is used, then the result has to include fuzzy rules.
- *Case based reasoning module.* Case based reasoning operates with “best practice” information that helps to reduce planning time as well as provides this information for researcher or user in explicit manner. As said above in complex environments there may be a while of unique situations. To extract (or to learn) any rule an intelligent system needs at least two equal (or similar – the most part of feature (attributes) are equal) situations. It means that in complex environments a while of situations experienced by the intelligent system may remain unused. Obviously, these unique situations (or cases) may be extremely valuable not only for the intelligent system but also for the modeler who uses the system. The case based reasoning module is involved to process and use these unique situations.
- *Associative reasoning module.* This module links objects according to similarities among object features as well as situations, thus allowing to reason associatively [Lit.5]. This module allows to reason about new situations or new objects using knowledge about similar objects or situations. It is an essential ability in complex and dynamic environments in order to increase a flexibility of the intelligent system.

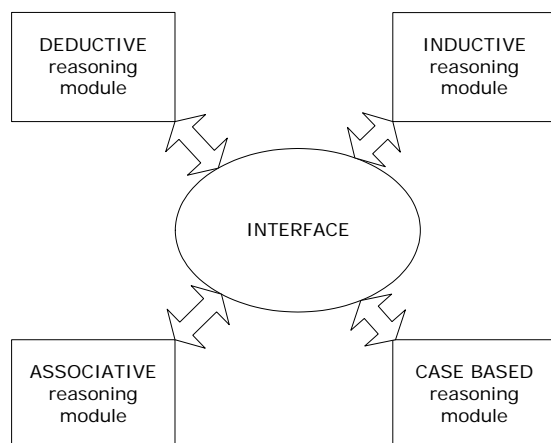


Figure 1. Basic modules

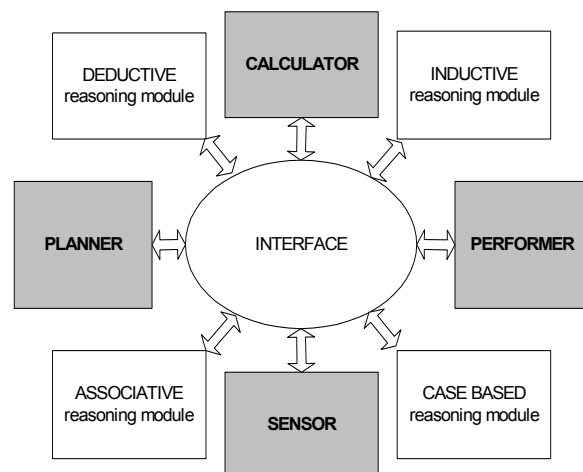


Figure 2 Enhanced structure

Of course, the intelligent system needs additional modules that would supply it with necessary information about the environment and mechanisms to perform some actions.

Therefore, the basic structure shown in figure 1 is complemented with additional modules. The enhanced structure is depicted in the figure 2.

The additional modules are drawn in gray. Each of the additional modules has the following basic functions:

- *Planner module.* This module is one of the central elements of the system. Its main function is to plan future actions that lead to achievement of goals of the system. On author's opinion, an ability to predict future events or situations in the most obvious manner demonstrates an intelligence of any more or less autonomous intelligent system. During the planning process three of the basic reasoning techniques are involved – deductive, case based and associative reasoning. A result of the planner is sequence of actions that are expected to be accomplished by the system thereby achieving its goals.
- *Sensor module.* The module's purpose is to collect information from system's sensors about environment and system's inner state. The sensed information is portioned in separate frames (see below) and forwarded to the interface (discussed later). Once the information is forwarded, it is available for other modules for readjustment of knowledge, for learning new knowledge or other purposes.

- *Performer module.* This module performs a sequence of actions that are listed in the plan. Also, this module uses information about current state of the system an environment in order to determine whether the instant actions can be accomplished. If not appropriate feedback information is sent to the sensor module.
- *Calculator module.* This module collects and produces any reasoning relevant quantitative data. For example, in both implementations (see below) this module is used to calculate certainties of rules including rules newly generated by the inductive reasoning module. Thus, this module is directly involved in knowledge readjustment process. Functionality of the module may be enhanced according to the necessities of the particular tasks or goals of the system's designer.

As it is depicted in figure 1, all of the four modules need some interface to communicate with each other therefore all of the modules use a central element – *Interface* in order to communicate to each other. They are not communicating to each other directly thereby a number of communication links is reduced as well as all of information circulating in the system is available for any module, if there is such a necessity.

A simplified structure of the interface is depicted in the following figure:

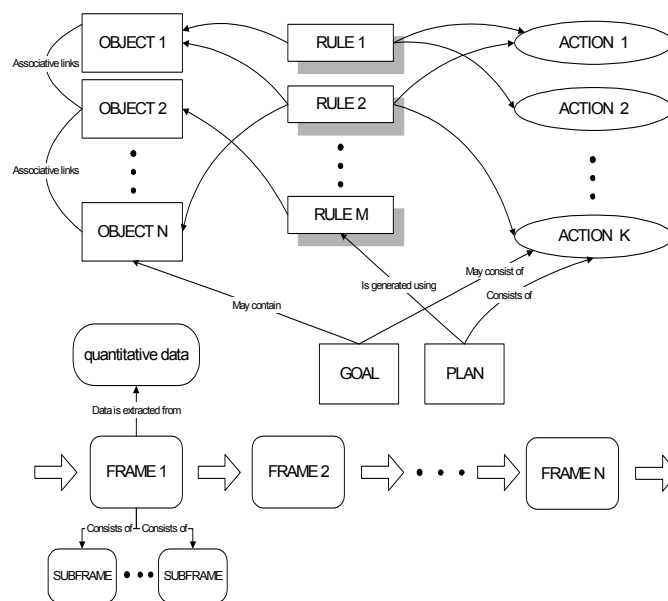


Figure 3 Structure of the interface.

The structure consists of several basic elements. The fundamental element of whole structure is *object*.

Object. Objects are key elements in the interface structure. They correspond to some kind of entities in the environment (or in the intelligent system). Every object is described with a set of features (attributes). Each feature has some value. As it is depicted in the figure 3 objects are linked to each other by associative links. These links form basis for associative reasoning.

When the intelligent system runs into a new situation some subset of objects is activated. These objects map to those entities that the intelligent system currently senses. If there is no rule that can be activated, then the intelligent system may try to activate associated objects. Thus, the system can try to reason about objects by using associated rules. The result may be less feasible, but using association among objects the system can run out of dead end situations.

A mechanism of associative memory is very useful when the system works with a noisy data. This mechanism allows to correct faults of the sensing mechanism [Lit.5,Lit.7]. For example, if the input vector of the sense, which corresponds to some entity, has some uncertain or incorrect elements (attributes of object) then the system would not be able to activate any of the objects. In this case associative memory mechanism will activate the closest object [Lit.5, Lit.7] thus the sensing error will be less significant to the reasoning process.

Rules. Rules are any kind of notation that represents causalities. In the practical experiments were used a well-known *if..then* notation. As it is depicted in the figure 3 rules are linked to objects and actions. When the system activates objects by using associative links linked rules also are activated thus system can scan a set of

“associated” rules as well. This ability improves system’s ability to adapt. Rules (for example, those of type *If..Then*) may refer not only to facts but also to actions. Thereby rules through deductive reasoning are used in planning process.

Actions. Actions are some kind of symbolic representation that can be translated by the intelligent system and cause the system to do something. For example “*turn to the right*” causes the system to turn to the right by 90°. Each action consists of three parts: precondition, body and postcondition. Precondition is every factor that should be true before the action is executed. For example, before opening the door it has to be unlocked. Body is a sequence of basic (or lower level) actions that are executed directly – for example a binary code that forwarded to motor controller causes the motors to turn (in a case of robotic system). Post conditions are factors that will be true after the execution of action. For example after opening the door, the door will be opened. It is important to stress that both implementations of the structure do not have any postcondition information at the beginning. All of the postconditions are learned during the system’s runtime.

Frames. Frames are some kind of data structures that contain the sense array from environment and from the system. It means that frames contain snapshots of the environment’s and the system’s states.

As it is depicted in figure 3 frames are chained one after another thus forming a historical sequence of the environment’s and the system’s states. Frames can be structured in hierarchies. Hierarchies help to see values of features that can’t be seen in a single snapshot. For example: motion trajectories of some object etc. Frames form an input data for learning (induction module) algorithms as well.

Goal. A goal is some kind of task that has to be accomplished by the system. It can be defined in three ways: as a sequence of actions that should be done, as some particular state that should be achieved or as a combination of actions and states. The third option is implemented in robotic systems described below.

Plan. Plan is a sequence of actions that is currently executed by the system (Performer module). It may be formed using both basic and complex actions. After the plan is accomplished, it is evaluated depending on whether the goal is achieved or not thereby forming a feedback information for calculator module.

Quantitative data. This element is used to maintain any kind of quantitative data that is produced by calculator module and is used during the reasoning process. For example, it may contain certainties about facts or rules, possibilities etc. Quantitative data is collected during the reasoning process as well as during the analysis of the input data - feedback data.

All of those components together form an interface for the basic modules: Inductive, Deductive, Case based and Associative reasoning.

Fundamental elements of the structure are implemented in experimental software and robotic systems that are shortly described below.

Experimental Software System

As it is mentioned above, fundamental elements of the proposed structure have found their implementation in experimental software systems. The implemented elements are: Case based reasoning, Inductive reasoning and Deductive reasoning. Deductive reasoning is implemented as a statement logic module based on rules designed in *if...then* manner. The induction module is implemented using very well known algorithm ID3 [Lit.9] It has its more effective successor C4.5 [Lit.10]. The case based reasoning module is implemented using pairs {situation, action}. Each of pair has its value that determines how effective it is in a particular case. During the planning this value determines which actions are selected if more then one action may be selected. The maximum length of the plan is limited in order to avoid infinite planning due to lack of a necessary knowledge for successive planning.

The environment is implemented as world of rabbits and wolf (domain of pray and hunter). There are defined additional objects “obstacles”. The number of rabbits and obstacles is not specified thus allowing definition of very complex configurations of the environment. The intelligent system is implemented as wolf. Rabbits may be moving or standing at one place. Wolf can catch rabbits. The wolf is moving according to its plan. Researcher (modeler) can freely change number and place of obstacles and rabbits during the system’s runtime thus acting as a stochastic element in the system’s environment. The goal also may be defined and changed at any time by the researcher (modeler).

The intelligent system demonstrates flexibility of the proposed structure. The results of experiments and experience accumulated during the implementation shows that new types of objects can be introduced without changing the proposed structure.

It means that even being incomplete this structure demonstrates good ability to adapt and to operate

Experimental Robotic System

The implemented robotic system is the next step of validation of the proposed structure.

Robotic system is a semi autonomous intelligent system that encapsulates all of the mentioned above elements of the proposed structure and interface among basic modules described above.

Mechanics

The system is a two-wheeled semi-autonomous robot. It has two driving or casting wheels and two auxiliary wheels for balancing. Casting wheels are driven by direct current motors equipped with planetary reducers.

The robot is equipped with the following sensors:

- Eight IR (infrared) range measuring sensors;
- Electronic compass;
- Four bump sensors (two front and two rear micro switches)
- Four driving wheel movement measuring resistors (two for each driving wheel in order to achieve reliable enough measurements).

Two Basix-X [Lit 15] microprocessors are used in order to communicate with PC and perform input data preprocessing and formatting. Processors communicate with each other via RS-232 connection.

Prepared and formatted data as frames (see above) are sent to PC also via RS-232 connection. All other modules of the intelligent system are implemented as PC-based software that has user-friendly interface allowing simple following the system's operation, collection of research sensitive data, changing system's goals etc....

Input

All sensed data is portioned in frames – one frame per second that is sent to PC via RS-232. In order to increase reliability the sensed data is preprocessed. The most important preprocessing is performed with IR ranger data because of the signal errors that should be eliminated. The IR sensors form so-called *situation* that consists of eight integer values. Each of the value describes distance to the closest object at one of eight directions.

Situation data is combined with other sensor data thereby forming an input data array that has the following structure:

[situation, compass, wheel 1 current position, wheel 2 current position, wheel 1 last position, wheel 2 last position, action, Bumper 1, bumper 2],

where:

Situation – eight integer values of ranges at appropriate directions;

Compass – System's orientation angel according to the Earth magnetic pole;

Wheel 1/2 current position – integer values that describes current position of the casting wheel

Wheel 1/2 last position – integer value that describes the last position of the casting wheel;

Bumper 1/2 – Boolean values that indicates whether an appropriate bumper switch is on (the robot has run onto obstacle);

Action – integer value that indicates the last action that has been performed;

The arrays are sent to PC each second. PC software stores incoming data into frames – one data array per frame.

Used basic algorithms

Inductive reasoning module:

This module is implemented using Quinlan's C4.5 inductive learning algorithm. One of the C4.5 features it that it requires a portion of data with static structure therefore as an input data a portion of frames is used. Each frame has a static structure. A sequence of frames is reformatted in the way that in one input data set record includes two frames – cause frame and consequence frame. For example:

Frame 1; Frame 2

Frame 2; Frame 3:

.....

Frame n; Frame n+1;

Frame n+1; Frame n+2;

Thus pairs of causes and consequences are formed therefore rules of type *If Cause Then Consequence* may be produced.

Obviously, the produced rules can describe events that follow right one after another. This is very important limitation of the proposed technical solution. Therefore, this issue is one of the future research directions in order to enhance the system with ability to reason about longer periods.

Deductive reasoning module:

This module is implemented via using forward chaining certainty factor reasoning technique. Rules are described in *if...then* manner. Each rule is evaluated with certainty factor that is obtained each time when new input action is accomplished by the robot and appropriate input frame is received. From the newly added frame the feedback information is obtained and certainty values of appropriate rules (that were used in order to plan the accomplished action during the planning process) are recalculated. Thus, the knowledge of the system is adjusted – via feedback information.

After induction when new rules are added, their certainty values are set to the maximum thus indicating that new knowledge is more valuable than the existing. If the new rule is conflicting with any existing rule, then certainty values of the existing rules are decreased, thus priority of the new rule during the deductive reasoning process is increased. This simple mechanism adds a capability to readjust knowledge according to the changing environment.

Associative reasoning module:

Associative reasoning module uses links among situations (each unique situation is stored in the interface data structure). If in the newly added frame a unique situation appears, then it is stored in the interface data structure. The new situation is linked to the similar situations. Similarities are determined by empirical algorithm.

During the deductive reasoning process, those links are used to select rules about similar situations if none of them is found about the actual situation. Thus, the system can reason associatively about certain situations if there is such a necessity.

Case-based reasoning module:

This module is used during the planning process. Cases are added after the feedback information about accomplished task (achieved goal) is received. Each case consists of the following parts: Goal, Situation and Plan. In other words, each case indicates what plan may be used in order to achieve certain goal in a certain situation.

Planner module:

This module combines deductive, case-based and associative modules in order to plan future actions that lead to achievement of the goal.

As it is possible to define a combined goal consisting of actions, and states sequenced one after another thus forming a sequence of subgoals, for each subgoal a subplan is produced. Planner can produce a plan only for a single goal or subgoal. A special algorithm is built that follows the plan execution during the runtime.

System's features

The PC-based software system implements and demonstrates all of the structure's elements mentioned above. The system is built for research purposes only in other words it is built for experiments in order to examine and validate the proposed structure. Therefore the system's user interface is built to be as flexible as possible allowing its user to manipulate with the robot's state, goals and results at the runtime.

The most important features of the system are:

- Ability to work with multiple goals with mixed structure that may include – actions, states or both;
- Ability to adapt via using inductive learning algorithm C 4.5[Lit.10].
- Case-Based reasoning is used to store information about best-practice cases and to use this information during the planning process.

- Ability to reason via using Certainty theory ideas thus allowing addition of new rules that may be conflicting with existing rules in the rule base.
- Ability to reason using associative links among objects (situations).
- The system's knowledge and system's state relevant data is stored and processed in explicit and easy to follow manner thus demonstrating advantages of the used knowledge based techniques.

It is important to stress that at the very beginning of the system's operation it has no information about consequences of each action – it needs to learn them. But if it is necessary the system's rule base may be filled with rules, cases and other research relevant information thus allowing to model some particular state of the system.

All of the necessary experiments are not finished yet - the system is under research process, but even the first experiments demonstrate very good ability of adaptation and learning new sequences of actions in order to achieve goals. All of the conceived experiments may be split in two major groups – experiments with goals that require matching of one action to one goal and goals that require more than one action in order to achieve the goal. Till now only the first group of experiments has been accomplished.

Possible Advances and Future Research

In order to queue actions one after another thereby building a sequence of actions that lead to achievement of the goal a planning module is used. The planning module is built as a classic single goal planner. If there is more than one goal, then the planner builds plans one by one for each goal. Usually for autonomous systems, there is a necessity to work with more than one goal at the same time, for instance, to follow the charge of batteries and to avoid obstacles. If the system is a team member, then the team's goals should be taken on account as well.

In a common situation, the avoidance of obstacles may have a higher priority than following the charge of batteries. If the battery charge is low then global priorities may change. In other words the system should be able to handle so-called global dynamics [Lit. 16] of the plans and their priorities. The mentioned ability is essential in such domains as robot soccer game or other similar very dynamic environments and complex.

The proposed structure cannot handle globally dynamic planning yet. This is one of directions for future research activities.

Obviously, may be there are tasks that cannot be accomplished using a single intelligent system. For example, simulation of some complex environments such as battlefields, transport systems etc. Therefore, there should be used more than one system, thus forming a multiagent environment.

There are different ways to design multiagent system [Lit.11, Lit 12]. In different domains, different solutions may be applied. Referencing to the said above, there may be outlined another direction of farther research and experiments – adjustments of the proposed structure in order to allow the intelligent system operate in a multiagent environment.

One of the most sophisticated problems in such a multiagent environment is communication because every communication parameter may be variable. It is easy to imagine that two intelligent systems may try to communicate using different knowledge representation schemas, different knowledge, different communication protocols, different type of “conversation” (for example: questioning, answering, argumentation etc.) or even different physical communication channels (radio frequency, verbal communication etc.) [Lit.13].

Another important direction of future research activities is adjusting the basic reasoning modules to allow reasoning about longer periods. That would allow planning actions for longer periods of time and to reason about events that could be caused by the system and would take a place after longer period as well.

Conclusions

Practical experiments show that the proposed structure may be very flexible even in very changing environments with variable goals. In both cases an adaptation and ability to learn is essential and both of them are persistent in the proposed structure. The proposed structure demonstrates capability to operate autonomously that makes it useful for autonomous robot control purposes.

In spite of the first results that are quite promising there are still some open questions that should be answered in the farther research activities.

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Author's Information

Agris Nikitenko – Doctoral student, Riga Technical University, Department of System theory, Meza street 1 k.4, Riga LV-1048, Lavtia, E-mail: agris.nikitenko@rembox.lv

INFORMATION MODELS FOR ROBOTICS SYSTEM WITH INTELLECTUAL SENSOR AND SELF-ORGANIZATION

Valery Pisarenko, Ivan Varava, Julia Pisarenko, Viktoriya Prokopchuk

Abstract: *It is chosen broad class of complex technical intellectualized systems with adaptation and self-training and some special properties of extremality. As example, the problem of adaptive control system for the scientific experiment with thermonuclear plasma is considered. The second example is connected with creation self-organizing mobile robot for examination emergency technical object on sea bottom.*

Keywords: *simulation modelling, autonomous mobile robots, self-training, aggressive ambience.*

Introduction

For performing a certain work in extreme condition and aggressive ambience, which is not compatible with health and safety of the person-operator, it is necessary to develop specialized robotics systems, including autonomous mobile robots with element of the artificial intelligence. Herewith for in stage of the designing as well as for the robot usages it is necessary to provide exchange by information between person and robot on language of the natural images about space, to form the certain images about external ambience with creation of knowledge-base, to provide the ability to self-training and adaptive control for a robot.