



EEG Based Brain Controlled Robot Using ARM7

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Abstract:

This project discussed about a brain controlled robot based on Brain-computer interfaces (BCI). BCIs are systems that can bypass conventional channels of communication (i.e., muscles and thoughts) to provide direct communication and control between the human brain and physical devices by translating different patterns of brain activity into commands in real time. With these commands a mobile robot can be controlled. The intention of the project work is to develop a robot that can assist the disabled people in their daily life to do some work independent on others. Brain signals will be sensed by the brain wave sensor and it will convert the data into packets and transmit through Bluetooth medium. Level analyzer unit (LAU) will receive the brain wave raw data and it will extract and process the signal using Matlab platform. Then the control commands will be transmitted to the robotic ARM module to process. With this entire system, we can pick an object and place it accordingly through the configured brain signals.

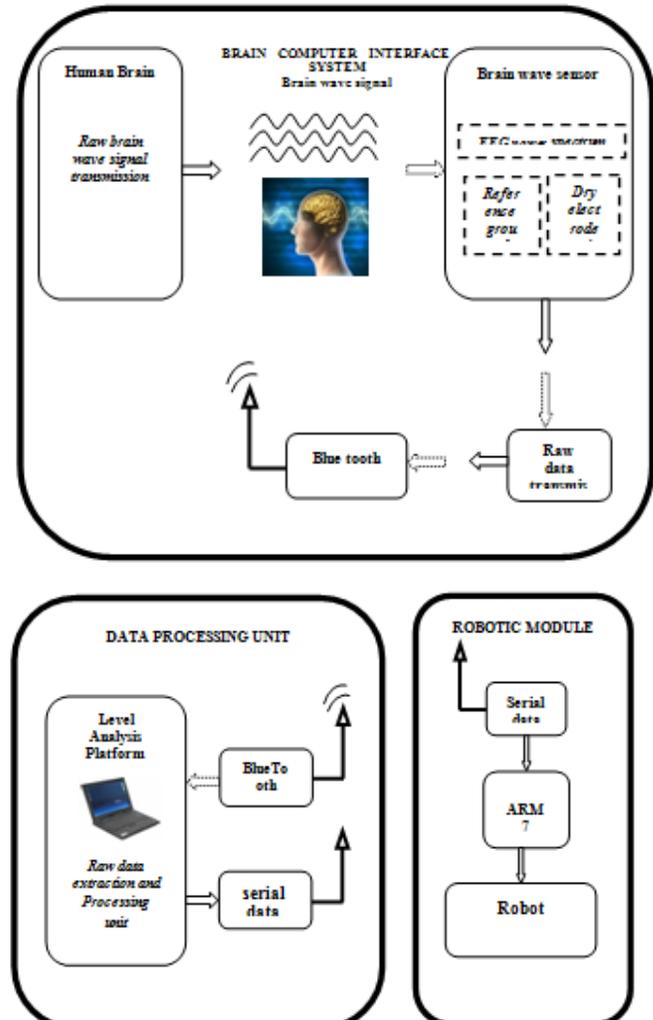
Keywords: ARM, BCI,

I. INTRODUCTION

An EEG-based brain-controlled robot is a robot that uses EEG-based BCIs to receive human control (hereafter, brain controlled robots refer to EEG-based brain-controlled robots only). Two main classes of brain-controlled robots to assist disabilities are brain-controlled manipulators and mobile robots. One representative work of brain-controlled manipulators is the manipulator used within the FRIEND system developed by Graser which is able to show the brain controlled capabilities of robots out of a controlled laboratory situation. Brain-controlled mobile robots can be divided into two categories according to their operational modes. One category is called "direct control by the BCI," which means that the BCI translates EEG signals into motion commands to control robots directly. Various approaches to implement this method are shown in Table I. One typical example is the work of Tanaka *et al.* [21], who first developed a brain-controlled robotic wheelchair whose left or right turning movements are directly controlled by corresponding motion commands translated from user brain signals while imagining left or right limb movements, and tested this system in real-world situations.

However, the overall performance of these brain-controlled mobile robots mainly depends on the performance of the noninvasive BCIs, which are currently slow and uncertain. In other words, the performance of the BCI systems limits that of the robots. Further, users need to issue motor control commands rather frequently, often causing user fatigue. To address the two questions aforementioned that the robots directly controlled by a BCI meet, so as to make the user be able to control the robot over a long period of time, the second group of brain-controlled robots has been developed from a perspective of shared control, where a user (using a BCI) and an intelligent controller (such as autonomous navigation system) share the control over the robots.

Block Diagram:

**Figure.1. BCI- Pick and Place**

II. DESIGN AND IMPLEMENTATION

Electroencephalography (EEG) is the measurement of electrical activity in the living brain. In this project we used a brainwave sensor MW001 to analyse the EEG signals. This design discusses about processing and recording the raw EEG signal from the Mind Wave sensor in the MATLAB environment and through Zigbee transmission control commands will be passed to the Robot section. Mindwave sensors are not used in clinical use, but are used in the Brain Control Interface (BCI) and neuro feedback (one of bio feedback types). The BCI is a direct communication pathway between the brain and an external device.

Working Principle:

The principle of operation is quite simple. Two dry sensors are used to detect and filter the EEG signals. The sensor tip detects electrical signals from the forehead of the brain. At the same time, the sensor picks up ambient noise generated by human muscle, computers, light bulbs, electrical sockets and other electrical devices. The second sensor, ear clip, is a ground and reference, which allows the think gear chip to filter out the electrical noise. The device measures the raw signal, power spectrum (alpha, beta, delta, gamma, theta), attention level, meditation level and blink detection. The raw EEG data received at a rate of 512 Hz. Other measured values are made every second. Therefore, raw EEG data is a main source of information on EEG signals using Mind Wave MW001.

Design Theory:

A. Matlab Platform:

The MATLAB allows to include thinkgear.dll. This environment has broad support in toolbox, which makes it ideal for a scientific research. This paper presents how recording and processing the raw EEG signal in MATLAB environment using MindWave sensor. The Communication Protocol, shows system of digital rules for message exchange between MATLAB environment and MindWave MW001 device. This section also presents the main parameters of think gearlibrary.

B. The Communications Protocol

The proposed communications protocol is a system of simple rules for message exchanges between MATLAB and the EEG device. It consists of 7 basic steps, which are presented in following steps.

- ❖ *Load Think Gear library into MATLAB*
- ❖ *Get a connection ID handle to ThinkGear*
- ❖ *Attempt to connect the connection ID handle to serial port "COMx"*
- ❖ *Waiting to establish the connection*
- ❖ *Read packets from the connection*
- ❖ *Close the connection*
- ❖ *Unload ThinkGear library*

In the first step are functions with parameters in the following order::

1. libisloaded ('Thinkgear') – returns true if the Think Gearlibrary is loaded, and false otherwise.

2. loadlibrary ('Thinkgear.dll','thinkgear.h') – loads the functions defined in the header file and found in the library. Now, the function calllib() can call a function in the ThinkGear library.

3. calllib('Thinkgear', 'TG_GetDriverVersion') – returns the version of loaded library.

In the next step, the function calllib('Thinkgear',' TG_GetNewConnectionId') gets a new connection ID handle to ThinkGear. The value -1 is returned if too many connections have been created.

In the ThinkGear library, the most important function is TG_Connect. This function needs 4 parameters: the connection ID, number of the serial port, Baud rate and type of data. The number of the serial port is given during the pairing of the device. The device can connect on modes 1200, 2400, 4800, 9600, 57600 and 115200 bits per second (bps). Here, we use the 9600 bps rate and stream 5V RAW mode, because these parameters have the minimum of transmission errors.

III. SYSTEM HARDWARE

LPC2148 Processor:

LPC2148 Microcontroller Architecture. The ARM7TDMI-S is a general purpose 32-bit microprocessor, which offers high performance and very low power consumption. The ARM architecture is based on Reduced Instruction Set Computer (RISC) principles, and the instruction set and related decode mechanism are much simpler than those of micro programmed Complex Instruction Set Computers (CISC). This simplicity results in a high instruction throughput and impressive real-time interrupt response from a small and cost-effective processor core. Pipeline techniques are employed so that all parts of the processing and memory systems can operate continuously. Typically, while one instruction is being executed, its successor is being decoded, and a third instruction is being fetched from memory. The ARM7TDMI-S processor also employs a unique architectural strategy known as Thumb, which makes it ideally suited to high-volume applications with memory restrictions, or applications where code density is an issue. The key idea behind Thumb is that of a super-reduced instruction set. Essentially, the ARM7TDMI-S processor has two instruction sets:

- The standard 32-bit ARM set.
- A 16-bit Thumb set.

The Thumb set's 16-bit instruction length allows it to approach twice the density of standard ARM code while retaining most of the ARM's performance advantage over a traditional 16-bit processor using 16-bit registers. This is possible because Thumb code operates on the same 32-bit register set as ARM code. Thumb code is able to provide up to 65% of the code size of ARM, and 160% of the performance of an equivalent ARM processor connected to a 16-bit memory system

- Standard 32-bit ARMv5TEset
- 16-bit THUMBset

1. Brain wave sensor

Electroencephalography (EEG) is the measurement of electrical activity in the living brain. In this project we used a brainwave sensor MW001 to analyse the EEG signals. This design discusses about processing and recording the raw EEG signal from the

MindWave sensor in the MATLAB environment and through Zigbee transmission control commands will be passed to the Robot section. Mindwave sensors are not used in clinical use, but are used in the Brain Control Interface (BCI) and neuro feedback (one of biofeedback types). The BCI is a direct communication pathway between the brain and an external device.

ThinkGear ASIC Module

- Directly connects to dry electrode (as opposed to conventional medical wet sensors)
- One EEG channel with three contacts: EEG; REF; and GND
- Improper fit detected through “Poor Signal Quality” warning from ASIC to reset if off the head for four consecutive seconds, or if it is receiving a poor signal for seven consecutive seconds
- Advanced filtering technology with high noise immunity
- Low power consumption suitable for portable battery-driven applications
- Max power consumption 15mA @ 3.3 V
- Raw EEG data output at 512 bits per second

Think Gear or TGAM Features + Technical Specifications

Measures

- Raw brainwave signal
- Processing and output of EEG power spectrums (Alpha, Beta, etc.)
- Processing and output of NeuroSky proprietary eSense meter for Attention, Meditation, and other future meters
- EEG/ECG signal quality analysis (can be used to detect poor contact and whether the device is off the head)
- Eyeblink detection

Electrodes

- Maximum surface area of ~150mm² (but less surface area is optimal)
- Ag/AgCl, Stainless Steel, Gold, or/and Silver (both solid and plated material works)
- EEG electrode located above the left or right eye on the forehead
- Ground and reference electrodes located behind the ear or at the earlobe
- Have enough pressure to prevent movement, with a minimum of 0.8 PSI

2. L293D

L293D is a dual H-bridge motor driver integrated circuit (IC). Motor drivers act as current amplifiers since they take a low-current control signal and provide a higher-current signal. This higher current signal is used to drive the motors. L293D contains two inbuilt H-bridge driver circuits. In its common mode of operation, two DC motors can be driven simultaneously, both in forward and reverse direction. The motor operations of two motors can be controlled by input logic at pins 2 & 7 and 10 & 15. Input logic 00 or 11 will stop the corresponding motor. Logic 01 and 10 will rotate it in clockwise and anticlockwise directions, respectively.

DC motor:

DC motors are configured in many types and sizes, including brush less, servo, and gear motor types. A motor consists of a rotor and a permanent magnetic field stator. The magnetic field is maintained using either permanent magnets or electromagnetic windings. Motors are the devices that provide the actual speed and torque in a drive system. This family includes AC motor types (single and multiphase motors, universal, servo motors, induction, synchronous, and gear motor) and DC motors (brush less, servo motor, and gear motor) as well as linear, stepper and air motors, and motor contactors and starters.

3. IEEE 802.15.4 Protocol:

The XBee/XBee-PRO RF Modules are designed to operate within the ZigBee protocol and support the unique needs of low-cost, low-power wireless sensor networks. The modules require minimal power and provide reliable delivery of data between remote devices. The modules operate within the ISM 2.4 GHz frequency band and are compatible with the following.

- Advanced Networking & Security
 - Point-to-point topology
 - point-to-multipoint topology
 - Self-routing, self-healing and fault-tolerant
 - mesh networking
 - Low Power
 - TX Current: 295 mA
 - RX Current: 45 mA
- Power-down Current: < 1 μ A

IV. SYSTEM SOFTWARE

MATLAB's Graphical User Interface Development Environment (GUIDE) provides a rich set of tools for incorporating graphical user interfaces (GUIs) in M-functions. Using GUIDE, the processes of laying out a GUI (i.e., its buttons, pop-up menus, etc.) and programming the operation of the GUI are divided conveniently into two easily managed and relatively independent tasks.

Role of Matlab in BCI:

The MATLAB allows to include thinkgear.dll. This environment has broad support in toolbox, which makes it ideal for a scientific research. This paper presents how recording and processing the raw EEG signal in MATLAB environment using MindWave sensor. The Communication Protocol, shows a system of digital rules for message exchange between MATLAB environment and MindWave MW001 device. This section also presents the main parameters of think gearlibrary. The connection is established through command:

```
calllib ('Thinkgear',' TG_Connect',Id, ComPortName ,TG_
BAUD_115200,TG_STREAM_ 5VRAW). In the next step, we
must attempt to read a Packet of data from the connection. We
use the TG_ReadPackets() function with ID parameter and
number of packet to read. The command calllib ('Thinkgear','
TG_ReadPackets',Id,1) returns false for error, and otherwise true.
The function TG_GetValueStatus() checks if a value has been
updated by TG_ReadPackets(). If this function returns true, we
```

canuse TG_GetValue() function to get the updated value of the raw EEG signal.

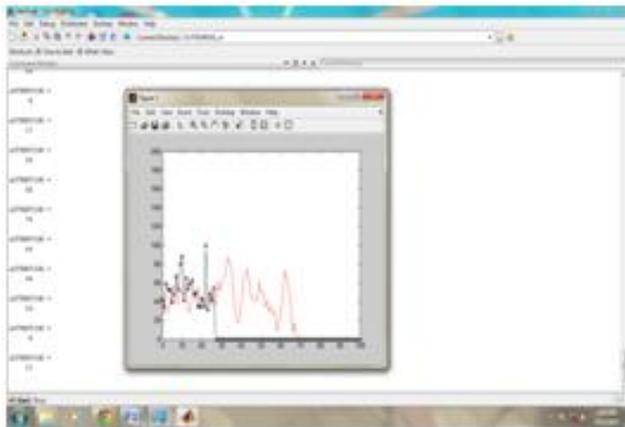


Figure.2. Brian signal representation in MATLAB

The above graph representation includes the attention value and blink strength. Based on this signals Pick and Place module will be controlled. Based on the brain signal commands the object will be picked and placed by the ARM module.

V. CONCLUSION

This project discussed about a brain controlled robot based on Brain-computer interfaces (BCI). BCIs are systems that can bypass conventional channels of communication (i.e., muscles and thoughts) to provide direct communication and control between the human brain and physical devices by translating different patterns of brain activity into commands in real time. With these commands an object can be picked and placed in any environment. This project will become an assistive technology for disabled people in future.

VI. REFERENCES

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