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[1] K. J. Jegadish Kumar
[2] S. V. Manikanthan
[3] Geetha Ramadas
[4] Bhupati
[5] Rakesh Kumar Giri

Robotic and Autonomous Systems (RAS): Dynamic Modeling of Cyber-physical Environments

Abstract: - Dynamic modeling of nonlinear systems in cyber-physical contexts is necessary for understanding and predicting complex behavior. Enabling accurate representation of intricate interactions between cyber and physical components is crucial for enhancing control systems, predicting maintenance requirements, and enhancing resilience. This article presents industrial automation and robotics, taking into account the circumstances in developing economies. The importance of studying and using industrial automation and robotics can be attributed to the complexity of today's industrial setup and the pressing demand for increased production quantity and quality. Finding current initiatives and chances for more research was the aim of the examination. When it reaches innovation maturity, there is a dearth of study on the application and adoption of automation technologies and even less on technology innovation or prototyping. A more recent development has been an increase in the amount of research being done on industrial production technologies, especially additive manufacturing. Research on non-robotic cyber-physical systems, such as IoT connection, drone technologies, and actuator and actuator technologies specifically geared towards the construction industry, is minuscule. This research significantly advances dynamic modeling methodologies by creating a comprehensive and adaptable strategy tailored to the complexities of cyber-physical systems.

Keywords: Automation and robotics, cyber-physical systems, IoT connection, Cyber.

I.INTRODUCTION

Infrastructure Robotic Systems (RAS) must function in a variety of challenging environments. For instance, robots in cities have to deal with the hazards posed by the intricate interactions between numerous people and cars, while robots in tunnels or mines have to deal with difficult terrain, constricted spaces, and impaired vision. Robots used in offshore and subsea infrastructure must be able to operate at depths under intense pressure and cold. Robots working on nuclear decommissioning also need to be able to tolerate radioactivity and limited access. Generally speaking, robots need to be resilient to strong pressures applied, resistant to dirt and dust, and able to withstand chemicals and materials used in construction. All of these situations have one thing in common: the robots require a high degree of independence with efficient self-monitoring, self-reconfiguration, and self-repair. This whitepaper describes the global trends in network robotics and our vision for the future, which calls for "zero" environmental impact and "zero" disruption to human activities in infrastructure maintenance [1]. It details UK investment and strategy in this important field as well as how we can cooperate to increase our competitiveness globally.

The purpose of the UK-RAS white papers is to provide a foundation for future technological roadmap discussions, include stakeholders and the larger community, and assist policymakers in evaluating the possible ethical, legal, social, and economic effects of RAS. We want to release annual revisions for these white papers, so your input is very important. You can highlight unintentionally left-out development areas that require attention or highlight significant emerging trends that demand more discussion and in-depth examination.

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[1] *Corresponding author: Associate Professor, Department of Electronics and Communication Engineering, Sri Sivasubramaniya Nadar College of Engineering, Chennai-603210. Email: jegadishkj@ssn.edu.in, ORCID: 0000-0002-9269-5908

[2] Director, Melange Academic Research Associates, Puducherry, India. Email: prof.manikanthan@gmail.com

[3] Professor, Electrical and Electronics Engineering, R. M. K. Engineering College, Kavaraipettai, Tamilnadu. Email: grs.eee@rmkec.ac.in

[4] Assistant Professor, Department of IoT, K L Deemed to be University, Vaddeswaram, Guntur-522302. Email: bhupati@kluniversity.in

[5] Assistant Professor, Department of Computer Science & Engineering, Sunrise University, Rajasthan. Email: rakesh274@gmail.com,

ORCID: 0009-0003-8082-835X

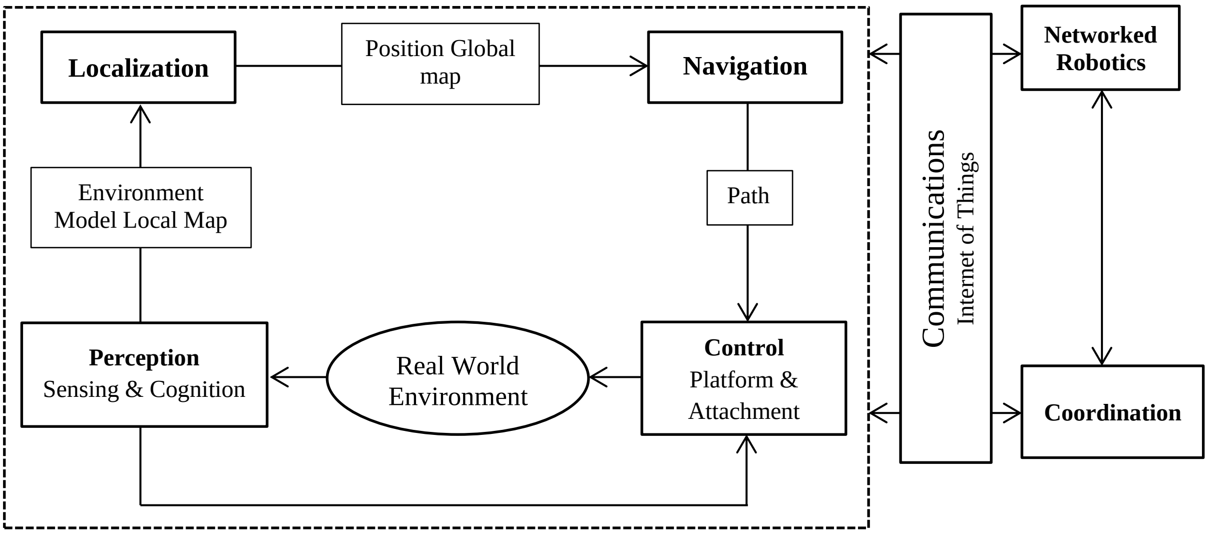

Figure 1.1. Fundamental Technologies Allowing Manufacture Equipment to Operate Autonomously

1.1. Army earthmoving core RAS technology

Depending on the kind, construction machines used in earthworks have different applications, but they frequently have the same basic design that consists of a mobile platform and an attachment. As a result, the fundamental technologies underlying those devices' autonomous operation are comparable to those of unmanned ground vehicles (UGVs), and they are depicted in the block diagram in Figure 1.1 [2]. The car uses perception to understand its sensors and derive useful information. To find its place in the ecosystem, each platform's activities need to be localized. When using navigation, a vehicle starts at one place, tracks its progress, and ends up at an endpoint. Control, in which the vehicle controls its actuators to accomplish a control target, is necessary to carry out an RAS-based process from lowest to higher levels. Technologies related to networked automation, data transmission, the Internet of Things, and platform coordination are needed for cooperative operations in the teleoperated, semiautonomous, and automated modes.

Due to greater customization, shorter product life cycles, and increasing rivalry from low-labor nations, many manufacturing organizations today operate in an uncertain and volatile manufacturing setting [3]. To stay competitive in this globalized market, they need to develop adaptable automatic solutions and adjust their manufacturing processes appropriately. Today's statically fixed factory robots, frequently arranged in a cell, carry out predetermined duties, enabling robot-based manufacturing to achieve the needed efficiency.

The remaining sections of the document are as follows: The status of nonlinear systems in cyber-physical environments is examined in the second section 2, along with the gaps in the body of extant work. Section 3 offers Analysing Nonlinear Systems (ANSC-PM), a cyber-physical modeling technique, as a potential remedy. The experiments' findings, analyses, and comparisons with previous approaches are shown in Section 4. Section 5 presents the final analysis and conclusion.

II.LITERATURE REVIEW

Robots are becoming more and more commonplace these days, with remarkable talents and robustness that allow them to care for, encourage, and even nurse humans. Specifically, a variety of duties, including personal care and medical treatment, can be carried out by robotic assistants. These robots are frequently referred to as service robots [4]. To do tasks, service robots usually interact with humans in their surroundings and display basic cognitive behavior. They are regarded as a subset of robot evolution and are expected to become a major area of study shortly. These days, manufacturing robots have become more adaptable and agile, in part because of their enhanced human-robot collaboration.

As a result of its intricate physical and informational operations—such as the science of combustibility, mechanical movement, fatigued material processes, processing information, clever data processing structures, and controlling movement through the use of technical vision—a robotic car is classified as a cyber-physical system [5]. It is expensive and impossible to take into account different scenarios and forecast the RTS's performance when designing such systems without building full-scale simulations. By studying models of the main units and components, indicating as a single complex, promising a model-based approach that allows the diagnosis and prediction of the RTS efficiency. In this regard, an effective way is to combine the implementation of digital models of gathers and parts RTS and carry a large number of digital examinations.

Robots in the future and the present day will be able to handle vast amounts of complex data, such as collected photographs and various kinds of sensor data. Recent communications advancements have made it possible for robots to record and upload sensory data to the cloud, thus enabling the IoT [6]. Since mobile and service robots have physical storage limitations by design, giving them access to distant cloud storage would enable them to post sensor data, fill distant databases, contribute to the creation and sharing of information bases, and carry out distant data analysis without requiring more onboard memory. Building knowledge bases for collaborative robot learning through the use of data generated by robots is a current research trend. Robots can share a collective intelligence space as a result of enhanced algorithms for object detection, robot path planning, and other areas.

RAS are frequently a component of self-adaptive autonomous systems (SAS), in which groups of heterogeneous systems are working together to accomplish shared objectives [7], like a convoy of vehicles. These systems dynamically reconfigure according to various changes, including unforeseen component or subsystem failures, ongoing operational context changes, varying workloads, and physical structures. SASs need to give assurance regarding their compliance with functional and non-functional criteria. Assurance for conventional non-adaptive systems is given by design and development processes that include certification, confirmation, evaluation, identification, and conformity to norms. Safety guarantees are frequently given through safety arguments, in which safety objectives are stated and justifications for thinking that these objectives are satisfied rely on several presumptions.

Dynamic Software Product Line ideas are the foundation of SmartyCo. A software product line, such as CPS, minimizes the work required to produce a family of software products. Products in this family differ based on changeable features and share common functionality or similarities. This variability is recognized by a domain expert and recorded in a variability model [8]. This variability model's features are translated into tangible, reusable software components that are combined to create the software item. Therefore, every CPS in SmartyCo DSPL is a product. A system can change its configuration while it is operating in a DSPL enabling binding variation at runtime. These concepts enable SmartCo to facilitate the adaption of these systems when necessary while handling the static setup of CPS for smart settings.

Almost two decades ago, a concept known as "homeostatic control" of electric power systems was put forth [9]. It differed from current practices in that it centered on the idea that all end users would modify their usage in actual time in reaction to local frequency and voltage variations; as a result, the system would balance in a completely decentralized manner. Transforming such ideas into actuality has proven to be an extremely difficult task that heavily depends on existing state regulations. Recently, there has been a significant re-examination of the concept of end users taking part in transmission congestion administration and, more recently, autonomous generation control. All of these concepts are essential to developing protocols for next-generation energy systems.

The resulting ideas of cognitive modeling, cognitive systems, cognitive designs, and systems that incorporate cognitive behavior are most frequently linked to the term "cognitiveness" in the context of the IT industry [10]. A strategy that supports decision-making by accounting for the relationships and reciprocal effects of different occurrences is known as cognitive modeling. With the aid of mental models and methods, cognitive analyses can quickly resolve problems like creating a situation model, evaluating the influence of internal and external variables on potential scenarios, and seeing patterns in the way situations evolve. Under unexpected conditions, management challenges are typically solved with the aid of cognitive modeling technologies. These human-inspired heuristic computations, discovered by biologists and psychiatrists who frequently work on development teams, are used by traditional systems with cognitive designs.

III.METHODS AND MATERIALS

3.1 The CPS processes' reason

BPMN describes how different participants behave when using distinct pools. A manufacturer is an example of a broader partner job, but it can also be a specific partner entity like a firm. Generally, the designers can partition the cyber-physical procedure model into lanes and pools to indicate which components or roles are in charge of carrying out certain process operations. Pools and lanes allow the designers to define the components of the system that carry out the various tasks and the structure of the procedure. The cyber-physical activity can be viewed as a collection of organized physical and cyber-activities arranged into three sections. The physical component carries out operations and gathers information from the external world. To make judgments, the computer portion gathers, examines, and saves information gathered by the physical part. The control portion collects sensory data, looks for computer services that are required, and initiates the physical activities.

On the other hand, it might occasionally be useful to depict a CPS as a cooperation diagram with several participants symbolized by pools. When a designer wants to be able to depict the CPS as a collection of interrelated procedures, where each process stands for a physical, control, or cyber component, they frequently use this model. If it becomes necessary to depict the various exchanges between CPS participants—which can be done through message exchanges—it might also make sense [11]. Message flows connecting the pools are used to mimic these communications. To provide more details, we break down the CPS cognitive model into many pools. Within the initial pool are the physical activities. The central controller that manages and coordinates the connection between the physical and cyber-processes is located in the third pool, while the cyber processes are located in the second pool. Therefore, a physical, control, and cyber process pool should be the minimum of several pools in a CPS architecture.

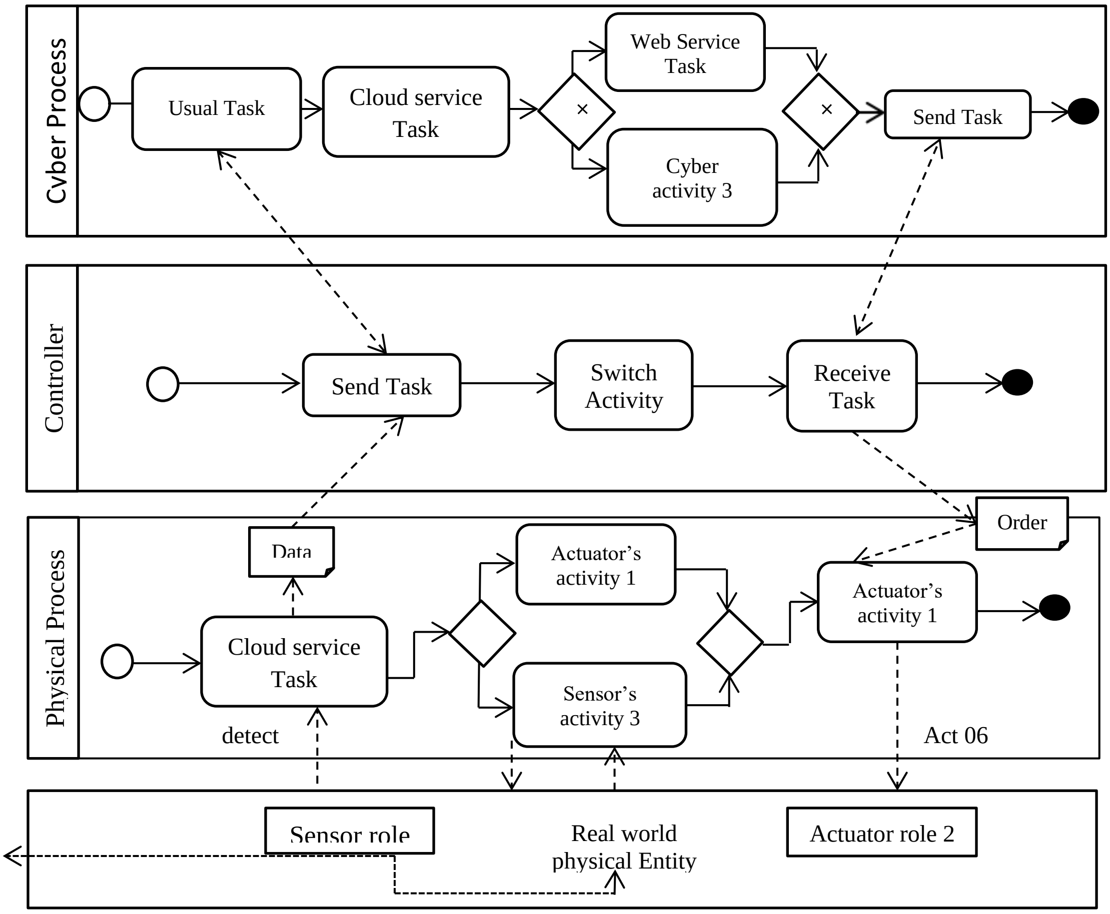

Figure 3.1. Three Processes are used to Model a CPS

As indicated by the label in Figure 3.1, the modeler is forced to explicitly represent the interaction between the tangible, oversight, and cyber systems by the division into process logic that is executed in each of them. Moreover, the data objects include details regarding the information generated by and/or the physical tasks that must be completed [12]. Figure 3.1 illustrates that the data items are the momentarily stored data of an instance of an ongoing process.

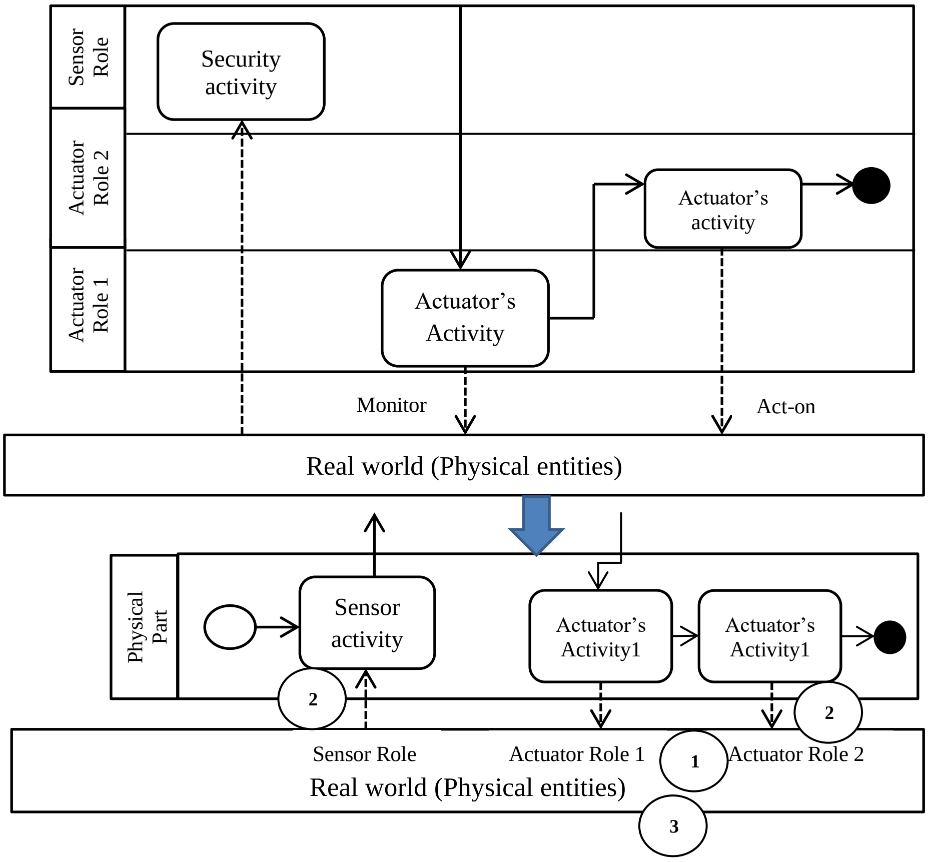

Figure 3.2. Definition of the Function of the Gadget

A physical entity within one process may be relevant for the physical operations of one or more CPS gadgets; we consider the RWE as a process applicant, except that it is not responsible for performed tasks. This extension is proposed to facilitate the requirements of the RWE, as an empty collection, which is a participant with various physical entities that can be influenced or tracked by an operational task. As shown in Figure 3.2, we designate the RWE as a black box pool with no internal details because of this. We note that the actual objects are passive aspects of the operation. These components are not in charge of any task; rather, their states are modifiable or measurable by the actions of an actuator or sensor.

Many definitions exist for our area, RAS; these definitions cover topics like autonomy (which includes sophisticated planning and decision-making), adaptation (which includes AI and machine learning), and interaction with humans and the external world. We believe that the definition that follows offers a succinct summary of these elements: An intelligent system that can function for lengthy periods without overt human involvement and interact with the physical environment on its own is called an autonomous system. They are designed to evaluate, take in, process, and respond to their surroundings.

The National Science Foundation and the Royal Academy of Engineering provided prior definitions [13], which served as inspiration for this one and had some complementary elements. Two crucial facets of this definition are emphasized here: the first is the system-level perspective, which means that software and hardware modules that are not autonomous machines in and of themselves will not be covered in our research; the second is its relationship with the environment, which means that autonomous systems that operate on offline data and lack interaction with their surroundings will also not be comprised.

3.2 Important Elements Influencing Ras's Credibility

Internationally, significant strategic efforts have been made to ensure that RAS is reliable. A trustworthy structure for cyber-physical systems, for instance, is offered by the US National Institute of Standards and Technology (NIST), and it addresses cyber security, confidentiality, security, dependability, and resiliency. To encourage the use of completely trustworthy RAS, the following features of its reliability need to be carefully examined. The system's autonomy in terms of sensing, data collection and processing, decision-making, communication, human-machine interaction, action control, and evaluation must provide strong support for its operation and efficiency. The fundamental need for autonomous systems is their logicalness, effectiveness, and reliability.

○ A major issue nowadays is security because more and more parts of life and business are going virtual. Cyber-attacks may directly jeopardize an autonomous system's security. Thus, any irregularities from cyber should be able to be detected, defended against, and avoided by RAS. RAS security is a subset of security that focuses on complying with laws (e.g., GDPR) and data protection, particularly the protection of private data. Industry 4.0 demands "security by construction" and "privacy by construction."

○ For all types of autonomous systems, safety is a constant demand. The need for safety in various autonomous system application sectors may vary. In certain systems (such as automobiles, aircraft, and buildings), safety is a crucial need. The safety and reliability of RAS are closely linked, making dependability a crucial consideration for humans when choosing an RAS. Security, safety, and both internal and external human and environmental interaction should all be co-designed.

○ In addition to the risks posed by the internet and external surroundings, possible process anomalies and component failures also pose a threat to the health, dependability, and security of RAS. Three types of failures can be identified in RAS: motor, detector, and plant problems. Therefore, it's critical to identify and detect a wide range of potential anomalies and errors as soon as feasible. You should also have fault-tolerant activities in place to minimize performance deterioration and prevent hazardous scenarios.

○ The term "human-machine interaction" describes how people and machines communicate and interact when using a user interface. Human input can be incorporated into the decision-making process in the NIST conceptual framework for Cyber-Physical Systems. Human communication should be based on observant and palpable user interface concepts, and systems should be able to be interrupted by humans regardless of their level of independence [14]. As a result of the system's automatic recognition of patterns over time, simple and effective visualization of sensed quantities, estimated statistics, and other data, users' self-efficacy and decision-making abilities may be enhanced. For the system to maintain the highest level of safety and dependability, the final two of Norman's seven HCI design principles—"Design for Failure" and "When everything else fails, standardize"—should be implemented.

IV.Implementation and Experimental Results

This comprehensive research, which strives to increase achievement, sustainability, system effectiveness, and flexibility, focuses on the dynamic modeling of nonlinear systems in cyber-physical environments. The article presents a novel approach to handling intricate relationships and real-time changes in networked ecosystems: analyzing Nonlinear Systems Cyber-Physical Modelling (ANSC-PM). Through the use of adaptive neural networks and complex mathematical frameworks [15], ANSC-PM can identify and adjust its operation in real-time in response to subtle behaviors.

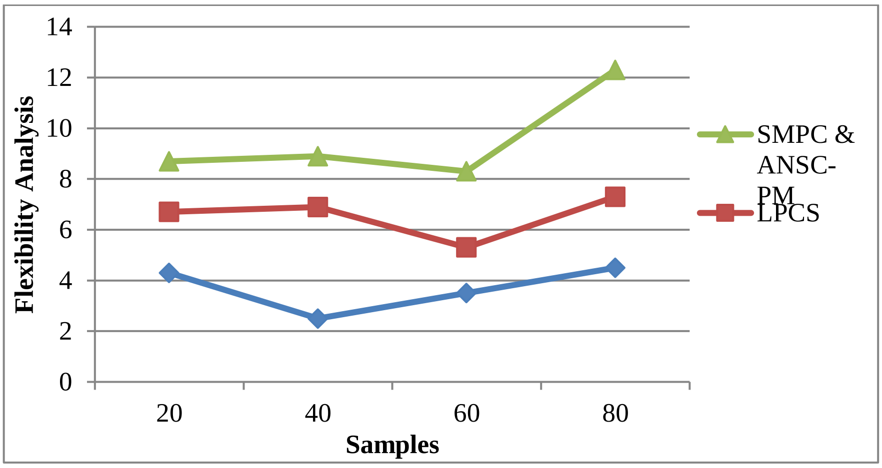

Figure 4.1. The Flexibility Analysis of ANSC-PM and DM-NS is Contrasted

This research on flexible assessment for dynamic modeling of complex structures in cyber-physical contexts shows how important adaptability is for understanding and predicting complex behaviors inside networked ecosystems. The research emphasizes how crucial dynamic modeling flexibility is for enhancing resilience, anticipating maintenance requirements, and controlling systems. The complexities of cyber-physical settings, which involve complex relationships and actual time changes, call for the use of modern modeling techniques [16]. Nonlinear System Analysis A proposed method called Cyber-Physical Modelling (ANSC-PM) combines complex mathematical representations and adaptable learning algorithms to accurately characterize nonlinear system behaviors and account for the dynamics of both cyber and physical components evolving. The ANSC-PM can be modified in real-time to remain relevant as the system changes, which helps address the issue of an uncertainty decrease in dynamic modeling.

This research has been beneficial to numerous domains, including robotic predictive maintenance, control system optimization, and enhanced resilience in networked environments. Through meticulous simulation research, the paper investigates the effectiveness of ANSC-PM, shedding light on its potential benefits for improving system durability, flexibility, and effectiveness. This study offers an extensive and flexible approach that is tailored to the complications of cyber-physical systems, which not only makes a significant contribution to dynamic modeling but also lays the foundation for the creation of strong and flexible strategies necessary for traversing the complexity of contemporary cyber-physical settings. With a score of 89.5 percent in Flexible Evaluation, ANSC-PM performs exceptionally well in comparison to other approaches in Figure 4.1. Conversely, DM-NS receives a score of 81.7% from the same assessment.

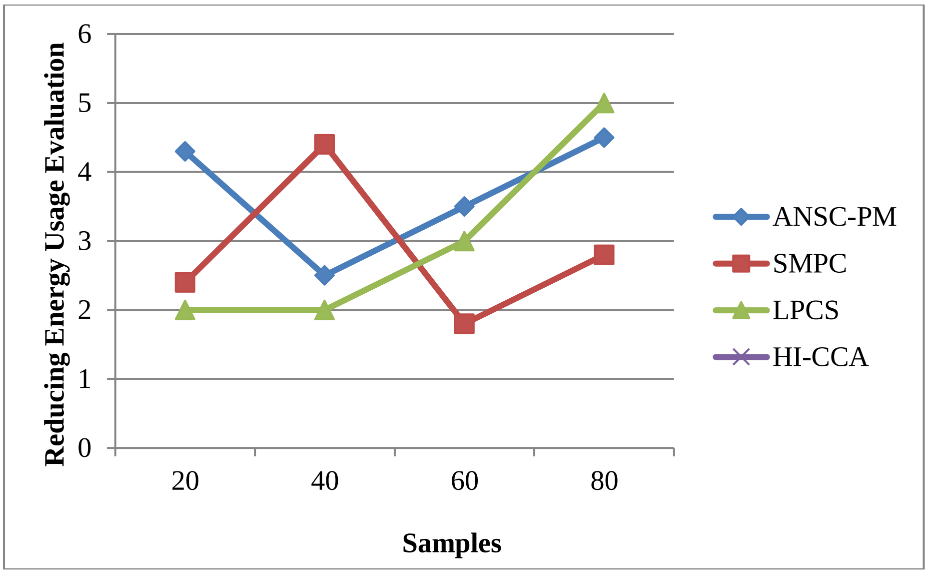

Figure 4.2. ANSC-PM and DM-NS are Contrasted in the Analysis of Minimizing Energy Consumption

This work explores the crucial element of energy consumption reduction during dynamic modeling of nonlinear structures within the framework of cyber-physical structures. The present research intends to explore strategies for optimizing energy consumption, given the increasing significance of energy efficiency in contemporary structures, particularly in connected environments. Cyber-physical environments have many moving components, and sophisticated modeling approaches are needed to properly depict these complex relationships and real-time changes. The proposed method, Analyzing Nonlinear Systems Cyber-Physical Modelling (ANSC-PM), uses complex mathematical models and adaptive learning algorithms to explain the behaviors of nonlinear structures. Priorities include understanding complex behaviors and anticipating them with little energy consumption. The flexibility of ANSC-PM to react in real-time ensures an optimal use of energy even as system dynamics alter. To determine how well ANSC-PM functions and what benefits it might offer for lowering power consumption without compromising the precision of dynamic models, this research thoroughly evaluates the technology using simulators. Beyond its value to dynamic modeling, the research has broader implications, especially for the development of energetic or cyber-physical structures. The study tackles the pressing need to reduce energy usage in dynamic modeling, laying the foundation for a paradigm shift towards more resource-efficient and ecological cyber-physical environments.

In the aforementioned figure 4.2, ANSC-PM outperforms rival approaches to get an outstanding effectiveness score of 25.7% in the Minimizing Energy Use Analysis. However, DM-NS can obtain a score of 22.5% in the same assessment.

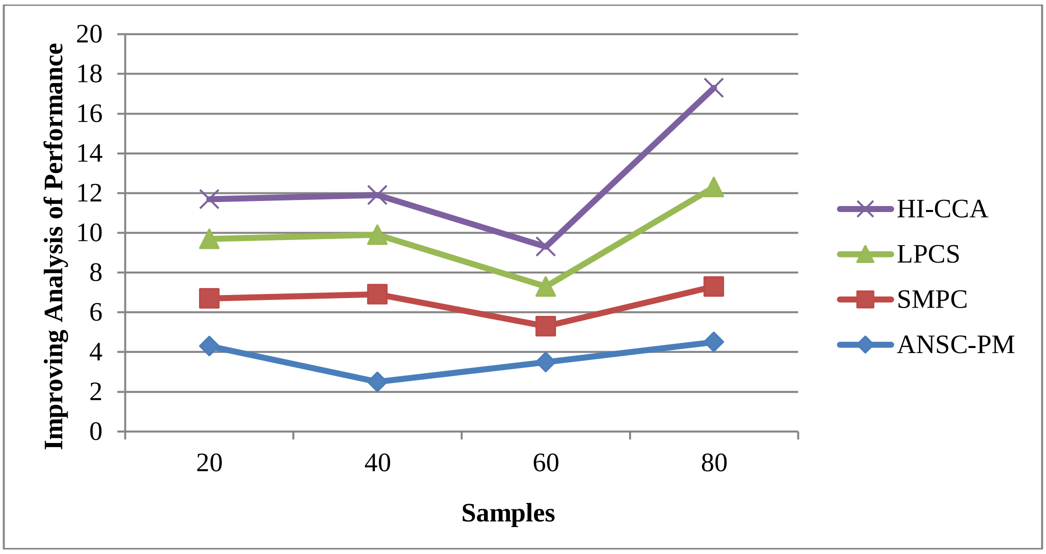

Figure 4.3. Comparison between ANSC-PM and DM-NS for Improving Performance Analysis

Figure 4.3 above illustrates how ANSC-PM outperforms rival approaches in the Improving Productivity Analysis, scoring 97.9% and more points than them. Nonetheless, DM-NS is able to obtain an impressive score of 95.4% in the same assessment. Enhancing the modelling of nonlinear structures in cyber-physical environments is the aim of the research in order to boost their efficiency. Optimizing performance is necessary to meet intricate interdependencies and react to real-time changes in connected ecosystems, and this is evolving quickly. The research tackles the complexity of cyber-physical environments with a focus on developing advanced modelling techniques that can accurately depict changing relationships. Through the unique integration of complex mathematical models with adaptable learning algorithms provided by our proposed technique, Analyzing Nonlinear Systems Cyber-Physical Modelling (ANSC-PM), users hope to better comprehend and predict complex behaviors while also improving overall system performance. ANSC-PM can respond to shifting system dynamics and optimize efficiency while optimizing resource usage by making real-time modifications. ANSC-PM and its potential benefits for enhancing dynamic model performance are assessed in this investigation using intensive computational modelling.

The implications of this work extend beyond its contribution to dynamic modelling in two domains: optimal control structures and robust networked ecosystems. This research has set the stage for strategies that, by placing an emphasis on performance enhancement, can significantly increase the general effectiveness and reactivity of cyber-physical systems. This can therefore enhance decision-making, reduce downtime, and boost flexibility in the face of shifting challenges. In many cyber-physical applications, it may ultimately result in an approach that is more effective and high performing.

Strong and adaptable methods are necessary for effectively negotiating the intricacy of today's cyber-physical scenarios, and our research lays the groundwork for these kinds of approaches. It has a significant impact on dynamic modelling. Given its superiority over existing methods in terms of reliability enhancement, cost effectiveness, system effectiveness, and flexibility, ANSC-PM is clearly the best choice.

V.CONCLUSION

Since at least four decades ago, related research has been conducted, and the construction sector has been utilizing robotic autonomous systems for almost fifty years. Many armed services are becoming more interested in utilizing RAS technologies in their construction projects. Specifically, as part of military operations, ground soldiers are often required to do earthwork tasks, which may be assisted entirely or in part by the use of RAS technologies. The automation of military construction has advanced rapidly thanks to the use of high-mobility ground-based platforms, data transmission systems, teleoperation and control systems, machine vision and influence abilities, human-machine and machine-machine interfaces, networked robotics, and cyber-physical systems.

Therefore, it is appropriate to conduct a broad analysis of these advancements with an eye on the following phase. With a focus on specific army applications, this study has provided a thorough overview and analysis of the technical viability, maturity, major technical obstacles, and future directions for the integration of RAS to earthmoving activities. In our analysis, we distinguish between different modes of control for typical automated platforms like digging machines, excavators, and front-end loaders, such as remotely operated, teleoperated, semi-autonomous, and autonomous operations. We also review modeling, low and high levels of control, their system architecture, recognizing and navigation, tool-soil interactions, simulation, and experiments from laboratory set-ups to full-scale field tests.

The proposed method, Analyzing Nonlinear Systems Hyperphysical Modelling (ANSC-PM), combines adaptive learning algorithms with sophisticated mathematical models to accurately characterize nonlinear system behaviors in complicated cyber-physical interactions. Enhancing the resilience of cyber-physical systems leads to better control systems and easier maintenance scheduling. As system dynamics increase, ANSC-PM's flexibility in real-time adjustments ensures its relevance, fulfilling the essential need for flexibility in dynamic modeling. This research has significant implications for numerous domains, including robotic predictive maintenance, resilience enhancement in connected settings, and control system optimization.

Extensive simulation studies validate the effectiveness of ANSC-PM, highlighting its benefits in improving system durability, flexibility, and efficiency. By developing a thorough and flexible plan for hyperphysical structures, this research considerably increases dynamic modeling techniques. Thus, control and optimization strategies—which are essential in the dynamic cyber-physical environment—are furthered.

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