



Introducing AI into MEMS can lead us to brain-computer interfaces and super-human intelligence

Journal:	<i>Assembly Automation</i>
Manuscript ID:	draft
Manuscript Type:	Viewpoint (journal staff only)



Review Only

Introducing AI into MEMS can lead us to brain-computer interfaces and super-human intelligence

David Sanders

David Sanders is a Reader in Systems & Knowledge Engineering based in the Faculty of Technology, University of Portsmouth, UK.

Keywords: intelligence, ambient, artificial, MEMS, micro-electromechanical, sensors.

Last year I spoke about the progress being made in machine intelligence^[1] and with sensors and networks of sensors^[2]. Earlier this year (in this journal) I spoke about ambient-intelligence, rapid-prototyping and the role of humans in the factories of the future^[3]. I addressed new applications and technologies such as merging machines with human beings, micro-electromechanics, electro-mechanical systems that can be personalized, smarter than human intelligence and swarms of smart sensors. Although the research to get us to all that will include human-machine interfaces, sensors, Artificial Intelligence (AI) and Ambient Intelligence (Aml), there is one technology above all others that has the potential to get us there fast... and that is the creation and development of intelligent micro-electromechanical machines (MEMS).

The potential of very small machines was appreciated long before the technology existed to actually make them. For example, the Nobel Laureate (Feynman) considered the ability to manipulate matter on an atomic scale^[4] and he concluded his 1959 talk with two challenges: first for anyone to build a tiny motor and second for anyone to write the information from a book page onto a surface 1/25,000 smaller. He offered prizes of \$1000 for each^[4]. The prize for the motor was won quickly using conventional tools but it was much later in 1985 when Tom Newman successfully reduced the first paragraph of "*A Tale of Two Cities*" and collected the second \$1000 prize^[5].

MEMS only became practical once they could be fabricated using modified semiconductor fabrication technologies such as moulding and plating, wet and dry etching and electro-discharge machining. MEMS are made up of components between 1 to 100 micrometres in size and MEMS devices are smaller than a millimetre long. They usually consist of a central microprocessor and other components that can interact with the outside world such as micro-sensors^[6]. At these sizes, the customary classical physics (that we are all used to) do not always hold true. Because of the much larger surface areas compared to volumes, surface effects such as electrostatics can dominate effects such as inertia or thermal mass. For example gravity becomes less important and instead Van der Waals attraction and surface tension can become more important.

MEMS devices will use less energy, space and time, and we will come to expect more and more output for less cost. Sensors and networks of sensors are already transforming manufacturing and assembly by scrutinizing our industrial environment and sometimes feeding into control systems to improve our processes. Individual sensors have tended to obtain data and then to transform that data into electrical signals to feed higher level systems^[2]. The development of such sensors has been driven by needs to reduce size and cost while increasing performance and MEMS could revolutionize the sensor markets by providing very small and very reliable devices at very little cost.

Until recently... sensors tended to be simple, unintelligent, connected directly into control systems, and static (or at best moved from place to place by separate transportation systems)... but all that is changing. Wireless networks are becoming more and more common and some smaller sensors

1 are becoming mobile so that networks of sensors can work in mobile teams (or swarms)^[2]. They
2 can deploy and locate themselves around a factory or a machine to efficiently sample (and
3 sometimes then control). Sensors are becoming “Smart Sensors” that can pre-process their own
4 data to improve quality and reduce communications. These sensors become really smart when
5 integral processing results in an adaptive sensing system that can react to external conditions and
6 still provide useful measurements in harsh manufacturing and assembly conditions. Our future
7 may be set to change through a combination of: smart mobile industrial sensors with enough
8 energy to change themselves within their environment (for example, to move themselves around);
9 effective wireless communication; automatic ranging; remote calibration; advances in
10 microprocessors; new algorithms; and reduced costs in some key areas^[2].
11

12 Increasing processing power within individual industrial sensors is improving the performance of
13 sensor arrays and allowing for more accurate sensing of some phenomena that have traditionally
14 required a large amount of off-line signal processing, such as image processing, sensor
15 integration and gas sensor arrays^[2]. As the information from numbers of sensor arrays becomes
16 larger (and therefore more complicated) then this leads to a need for systems to model and then
17 convey the information in a simple way (and sometimes in real time) to human beings. These
18 electronic sensor systems and their components are sometimes exposed to harsh environmental
19 conditions and some new industrial sensors could be especially robust in harsh conditions. For
20 example, some MEMS-sensors appear to be able to withstand very high humidity, pressure and
21 temperature and these sensors-on-a-chip are potentially low cost^[2].
22
23
24

25 Meanwhile, AI systems have been improving for a decade^[1,3,7] and Aml for assembly and
26 manufacturing has been developing slowly^[3,8,9]. They promise to bring improvements in flexibility,
27 reconfigurability and reliability. Machine Intelligence combines a wide variety of advanced
28 technologies to give machines an ability to learn, adapt, make decisions and display new
29 behaviours^[1,3]. This is achieved using technologies such as neural networks^[10-14], expert
30 systems^[15-18], self-organizing maps^[2,19], fuzzy logic^[3,20] and genetic algorithms^[1,21] and that
31 machine intelligence technology has been developed through its application to many areas, such
32 as: assembly^[3,13,22,23], building modelling^[3, 24,25], computer vision^[13,26-30], environmental
33 engineering^[2,31-35], human-computer interaction^[12,14,36-38], internet use^[39,40], powered-wheelchair
34 assistance^[41-44], maintenance and inspection^[45,46], medical systems^[37,41,47], robotic
35 manipulation^[11,18,48,49], robotic programming^[18, 50-55] and sensing^[2,7,28,58-60].
36
37
38
39

40 Our machines are exceeding human performance in more and more tasks (from guiding objects to
41 assembling other machines) and some developments in machine intelligence are already being
42 introduced into new manufacturing methods such as rapid-manufacture^[3] and the manufacture of
43 composites^[61-63]. If they can be effectively introduced into MEMS devices and into the
44 manufacture of MEMS devices then machines can be made to merge with us more intimately and
45 we should be able to combine our brain power with computer capacity to create a powerful
46 artificial intelligence. It is difficult to see the boundaries to what may be possible then and some
47 scientists are predicting a period when the pace of technological change will be so fast and far-
48 reaching that our lives will be irreversibly altered^[1]. At that point we may need a different type of
49 engineer^[64, 65].
50
51
52

53 There are some interference problems that might become critical for wireless communications
54 between MEMS and they can also be limited by antenna size, power and bandwidth, and that is
55 all being explored by some radio engineers. MEMS will need the ability to cope with technology or
56 communication failures and large scale deployments and large amounts of data will need new
57 computer science algorithms. The computer scientists are investigating some of that. The big
58 future problems for MEMS may include constraints on resources such as energy, memory,
59 computational speed and bandwidth. These limitations really push research towards distributed
60 energy-efficiency. It is that potential need for smaller and more energy efficient sensors that can

operate autonomously in harsh industrial conditions that will drive research towards more robust and fault tolerant MEMS that can automatically compensate for variables such as temperature.

For the immediate and medium term future, useful advances will come from research into: human-machine interfaces, sensors, AI, Aml, modelling, and improving MEMS manufacturing and design techniques. In the longer term, understanding the properties of MEMS materials and then creating more capable and intelligent MEMS machines will lead to direct brain-computer interfaces that will allow us to communicate our ideas directly to machines (and to other human members of virtual teams) and that may change our world beyond recognition.

References:

1. Sanders, D (2008). Progress in machine intelligence. *Industrial Robot – an international journal* 35, 6, pp 485-487.
2. Sanders, D (2008). Environmental sensors and networks of sensors. *SENSOR REVIEW* 28 (4), pp 273-274.
3. Sanders DA (2009) Ambient Intelligence and energy efficiency in rapid prototyping and manufacturing. *Assembly Automation paper AA 29:3 (In press)*.
4. Feynman RP (1960). There's Plenty of Room at the Bottom; an Invitation to Enter a New Field of Physics. *Caltech's Engineering and Science XXIII* (5) pp. 22-36 (February 1960 issue). *Also on the web at:* <http://www.zyvex.com/nanotech/feynman.html>
5. Gribbin J (1997). *Richard Feynman: A Life in Science*, Dutton 1997, pg 170.
6. Waldner, JB (2008). *Nanocomputers and Swarm Intelligence*. London: ISTE John Wiley & Sons. pp. p205. ISBN 1847040020.
7. Sanders, D (1999). Perception in robotics. *Industrial Robot – an international journal* 26 (2), pp 90-92.
8. Sanders DA, Liu H, Harrison DJ and Gegov A (2008). Energy Efficiency based on Ambient Intelligence. *Journal of computing in systems and engineering*, 9 (1), pp 114 – 120. ISSN 1472-9083.
9. Riva G, Vatalaro F, Davide F & Alcañiz M (Eds) (2005). *Ambient Intelligence in Practice: Future Perspectives and Applications*. IOS Press, pp.237-264.
10. Sanders DA, Haynes BP, Tewkesbury GE, et al. (1996). The addition of neural networks to the inner feedback path in order to improve on the use of pre-trained feed forward estimators. *Mathematics and computers in simulation* 41 (5-6), pp 461-472.
11. Urwin-Wright S, Sanders D, Chen S (2003). Predicting terrain contours using a feed-forward neural network. *Engineering Applications of Artificial Intelligence* 16 (5-6), pp 465-472.
12. Sanders DA, Urwin-Wright SD, Tewkesbury GE, et al (2005). Pointer device for thin-film transistor and cathode ray tube computer screens. *Electronics Letters* 41 (16), pp 894-896.
13. Sanders DA (2009). Recognizing shipbuilding parts using artificial neural networks and Fourier descriptors. *Proc. IMechE, Part B: J. Engineering Manufacture*, 2009, 223(B3), 337–342.
14. Sanders DA (2009). A pointer device for TFT display screens that determines position by detecting colours on the display using a colour sensor and an Artificial Neural Network, *Displays Paper DISPLA-D-08-00006, DISPLAYS Volume: 30 Issue: 2 Pages: 84-96 Published: 2009*.
15. Hudson AD, Sanders DA, Golding H, et al. (1997). Aspects of an expert design system for the wastewater treatment industry. *Jnl of Systems Architecture* 43 (1-5): 59-65.
16. Sanders DA and Hudson AD (2000). A specific blackboard expert system to simulate and automate the design of high recirculation airlift reactors. *Mathematics & Computers in simulation* 53 (1-2), pp 41-65

17. Sanders, DA; Hudson, AD; Tewkesbury, GE, et al (2000). Automating the design of high-recirculation airlift reactors using a blackboard framework. *EXPERT SYSTEMS WITH APPLICATIONS* 18 (3), pp 231-245.
18. Tewkesbury G and Sanders D (1999). A new robot command library which includes simulation. *Industrial Robot: An International Journal* 26 (1), pp 39-48.
19. Burn K, Home G (2008). Environment classification using Kohonen self-organizing maps. *Expert Systems* 25 (2), pp 98-114.
20. Zoumponos GT, Aspragathos NA (2008). Fuzzy logic path planning for the robotic placement of fabrics on a work table. *Robotics and computer-integrated manufacturing* 24 (2), pp 174-186.
21. Manikas TW, Ashenayi K, Wainwright RL (2007). Genetic algorithms for autonomous robot navigation *IEEE Instrumentation & Measurement, Vol: 10 (6)*, pp 26-31. ISSN: 1094-6969.
22. Schraft RD and Ledermann T (2003). Intelligent picking of chaotically stored objects. *Assembly Automation* 23 (1), pp 38-42
23. Guru SM, Fernando S, Halgamuge S and Chan K (2004). Intelligent fastening with A-BOLT technology and sensor networks. *Assembly Automation* 24 (4), pp 386 – 393.
24. Gegov, A (2004). Application of computational intelligence methods for intelligent modelling of buildings. *Applications and science in soft computing* ISSN: 1615-3871 (Advances in soft computing ISBN: 3-540-40856-8 Editors: Loffi A, Garobaldi J), Springer-Verlag, Berlin, pp 263-270.
25. Wong J, Li H, Lai J (2008). Evaluating the system intelligence of the intelligent building systems *Automation in construction* 17 (3), pp 303-321.
26. Bertozzi M, Bombini L, Broggi A, Cerri P, Grisleri P, Medici P, Zani P (2008). GOLD: A framework for developing intelligent-vehicle vision applications. *IEEE Intelligent Systems. Vol: 23 (1)*, pp 69-71.
27. Chester, S; Tewkesbury, G; Sanders, D, et al (2007). New electronic multi-media assessment system. *Web Information Systems and Technologies* 1, pp 414-420.
28. Sanders DA (1993). System specification 2. *Microprocessing and microprogramming* 38 (1-5), pp 833-834.
- 29: Sanders DA, Harris P and Mazharsolook E (1992). Image modelling in real time using spheres and simple polyhedra. *4th Int Conf on Image Processing and its applications. Vol 354*, pp 433-436.
30. Chester, S; Tewkesbury, G; Sanders, D, et al (2006). New electronic multi-media assessment system. *WEBIST 2006: Proceedings of the Second International Conference on Web Information Systems and Technologies*, pp 320-324.
31. Hinks JW, Cawte H, Sanders, DA, et al (1996). Prediction of flow rates and stability in large scale airlift reactors. *Water science and technology* 34 (5-6), pp 51-57.
32. Sanders DA, Cawte H and Hudson AD (2001). Modelling of the fluid dynamic processes in a high-recirculation airlift reactor. *Int Jnl of Energy Research* 25 (6), pp 487-500.
33. Hudson, AD; Sanders, DA; Tewkesbury, GE, et al (1996). Simulation of a high recirculation airlift reactor for steady-state operation. *Water science and technology* 34 (5-6), pp 59-66.
34. Sanders, DA; Hudson, AD, Cawte H, et al (1994). Computer modelling of single sludge systems for the computer-aided design and control of activated sludge processes. *Microprocessors and microprogramming* 40 (10-12), pp 867-870.
35. Hinks JW, Cawte H, Sanders DA, et al (1995). Model for the prediction of liquid volumetric flow rates in large scale airlift reactors. *3rd Int Conf on water and waste treatment. Book Series: BHR GROUP CONFERENCE SERIES. Issue:17*, pp 125-133.
36. Sanders DA and Baldwin A (2001). X-by-wire technology. *Total vehicle technology: Challenging current thinking*, pp 3-12.

- 1 37. Stott I, Sanders D (2000). The use of virtual reality to train powered wheelchair users and test new wheelchair
2 systems. *Int Jnl of Rehab Research* 23 (4), pp 321-326.
- 3 38. Zhao M, Nowatzky AG, Lu T, Farkas DL (2008). Intelligent non-contact surgeon-computer interface using hand
4 gesture recognition. *Three dimensional image capture and applications 2008, Proc of SPIE-IS&T Electronic Imaging,*
5 *Vol: 6805, pp U8050-U8050.*
- 6 39. Bergasa-Suso J, Sanders DA, Tewkesbury GE (2005). Intelligent browser-based systems to assist Internet
7 users. *IEEE Transactions* 48 (4), pp 580-585.
- 8
- 9 40. Kress M (2008). Intelligent Internet knowledge networks: Processing of concepts and wisdom. *Information*
10 *processing & management. Vol: 44 (2), pp 983-984.*
- 11
- 12 41. Sanders DA and Stott IJ (1999). A new prototype intelligent mobility system to assist powered wheelchair users.
13 *Industrial Robot: An International Journal; Vol: 26 (6), pp. 466-475*
- 14
- 15 42. Stott IJ, Sanders DA and Goodwin MJ (1997). A software algorithm for the intelligent mixing of inputs to a tele-
16 operated vehicle. *Jnl of systems architecture* 43 (1-5), pp 67-72.
- 17
- 18 43. Goodwin, MJ; Sanders, DA; Poland, GA, et al. (1997). Navigational assistance for disabled wheelchair-users *Jnl*
19 *of systems architecture* 43 (1-5), pp 73-79.
- 20
- 21 44. Pei J, Huosheng H, Tao L and Kui Y (2007). Head gesture recognition for hands-free control of an intelligent
22 wheelchair. *Industrial Robot: An International Journal* 34 (1), pp 60–68.
- 23
- 24 45. Nadakatti, M; Ramachandra, A; Kumar ANS (2008). Artificial intelligence-based condition monitoring for plant
25 maintenance. *Assembly Automation* 28 (2), pp 143-150.
- 26
- 27 46. Anon (2008). An intelligent inspection solution for smarter seating. *Assembly Automation* 28 (2), pp 173-173.
- 28
- 29 47. Ohbayashi K (2008). Advanced Cancer Research with PXI and LabVIEW. *Instrumentation Newsletter, Issue Q3,*
30 *p29.*
- 31
- 32 48. Bullinaria, JA; Li, XL (2007). An introduction to computational intelligence techniques for robot control. *Industrial*
33 *robot – an international journal* 34 (4), pp 295-302.
- 34
- 35 49. Sreekumar M, Nagarajan T, Singaperumal M, Zoppi M and Molfino R (2007). Critical review of current trends in
36 shape memory alloy actuators for intelligent robots. *Industrial Robot: An International Journal* 34 (4), pp 285 – 294.
- 37
- 38 50. Tewkesbury GE and Sanders DA (1994). The automatic programming of production machinery for de-flashing
39 plastic parts. *Advances in manufacturing technology VIII, pp 279-283.*
- 40
- 41 51. Urwin-Wright, S; Sanders, D; Chen, S (2002). Terrain prediction for an eight-legged robot. *Jnl of robotic systems*
42 *19 (2), pp 91-98.*
- 43
- 44 52. Tewkesbury GE and Sanders DA (2001). The use of distributed intelligence within advanced production
45 machinery for design applications. *Total vehicle technology: challenging current thinking, pp 255-262.*
- 46
- 47 53. Sanders DA and Rasol Z (2001). An automatic system for simple spot welding tasks. *Total vehicle technology:*
48 *challenging current thinking, pp 263-272 Published: 2001*
- 49
- 50 54. Bogue, R (2008). Swarm intelligence and robotics. *Industrial robot – an international journal* 35 (6), pp 488-495.
- 51
- 52 55. Tewkesbury G, Sanders D (1999). A new simulation based robot command library applied to three robots.
53 *Journal of robotic systems* 16 (8), pp 461-469.
- 54
- 55 56. Sanders DA (1995). The modification of pre-planned ROBOTICA 13, pp 77-85.
- 56
- 57 57. Sanders DA (1995). Real time geometric modelling using models in an actuator space and Cartesian space.
58 *Journal of robotic systems* 12 (1), pp 19-28.
- 59
- 60 58. Sanders D (2007). Viewpoint - Force sensing. *Industrial Robot: An International Journal* 34 (4), pp 268-268.

- 1
2
3
4
5
6
7
8
9
10
11
12
13
14
15
16
17
18
19
20
21
22
23
24
25
26
27
28
29
30
31
32
33
34
35
36
37
38
39
40
41
42
43
44
45
46
47
48
49
50
51
52
53
54
55
56
57
58
59
60
59. Sanders (2008). Controlling the direction of “walkie” type forklifts and pallet jacks on sloping ground. *Assembly Automation* 28 (4), pp 317–324.
60. Stott I, Sanders D (2000). New powered wheelchair systems for the rehabilitation of some severely disabled users. *Int Jnl of rehabilitation research* 23 (3), pp 149-153,
61. Zhang, ZY; Richardson, MOW (2007). Low velocity impact induced damage evaluation and its effect on the residual flexural properties of pultruded GRP composites. *Composite structures* 81 (2), pp 195-201.
62. Wang, W; Song, M; Zhang, ZY, et al (2006). Synthesis and characterization of high nickel-containing mesoporous silica via a modified direct synthesis method. *Jnl of non-crystalline solids* 352 (21-22), pp 2180-2186.
63. Ferreira, JM; Pires, JTB; Costa, JD, et al (2007). Fatigue damage and environment interaction of polyester aluminized glass fiber composites. *Composite structures* 78 (3), pp 397-401.
64. Sanders D and Harrison DJ (1992). The requirement for integrated and systems engineers in a complex and flexible future. *Engineering education* 3, pp 343-348.
65. Harrison DJ and Sanders D (1992). Imagineering – promoting creativity in engineering education. *Engineering education* 2, pp 45-49.

Review Only