

# The memristive artificial neuron high level architecture for biologically inspired robotic systems

Talanov M., Zykov E., Erokhin V., Magid E., Distefano S.  
*Kazan Federal University, 420008, Kremlevskaya 18, Kazan, Russia*

---

## Abstract

© 2017 IEEE. In this paper we propose a new hardware architecture for the implementation of an artificial neuron based on organic memristive elements and operational amplifiers. This architecture is proposed as a possible solution for the integration and deployment of the cluster based bio-realistic simulation of a mammalian brain into a robotic system. Originally, this simulation has been developed through a neuro-biologically inspired cognitive architecture (NeuCogAr) re-implementing basic emotional states or affects in a computational system. This way, the dopamine, serotonin and noradrenaline pathways developed in NeuCogAr are synthesized through hardware memristors suitable for the implementation of basic emotional states or affects on a biologically inspired robotic system.

<http://dx.doi.org/10.1109/ICMSC.2017.7959470>

---

## Keywords

affects, artificial neuron, biologically inspired robotic system, circuits, Cognitive architecture, memristive elements

## References

- [1] J. E. Laird. (2008) Extending the soar cognitive architecture. University of Michigan.
- [2] A. V. Samsonovich, Modeling human emotional intelligence in virtual agents, AAAI Fall Symposium-Technical Report, vol. FS-13-03. AI Access Foundation, 2013, pp. 71-78.
- [3] J. Vallverdu, M. Talanov, S. Distefano, M. Mazzara, A. Tchitchigin, and I. Nurgaliev, A cognitive architecture for the implementation of emotions in computing systems, Biologically Inspired Cognitive Architectures, Nov 2015.
- [4] H. Lövheim, A new three-dimensional model for emotions and monoamine neurotransmitters, Medical hypotheses, vol. 78, no. 2, pp. 341-348, Feb 2012.
- [5] R. Khusainov, I Afanasyev, L Sabirova, and E Magid. Bipedal robot locomotion modelling with virtual height inverted pendulum and preview control approaches in Simulink environment. J. of Robotics, Networking and Artificial Life, vol. 3 (3), Atlantis Press, pp. 182-187, 2016.
- [6] L. Lanari, S. Hutchinson, and L. Marchionni, Boundedness issues in planning of locomotion trajectories for biped robots, IEEE-RAS Int. Conf. on Humanoid Robots, pp. 951-958, 2014.
- [7] N. Kofinas, E. Orfanoudakis, and M. G. Lagoudakis, Complete analytical forward and inverse kinematics for the NAO humanoid robot, J. of Intelligent & Robotic Systems, 77 (2), 251-264, 2015.
- [8] K. Ramirez-Amaro, E. Dean-Leon, and G. Cheng, Robust semantic representations for inferring human co-manipulation activities even with different demonstration styles. IEEE-RAS Int. Conf. on Humanoid Robots, pp. 1141-1146, 2015.

- [9] R. Khusainov, A. Sagitov, A. Klimchik, and E. Magid. Modelling of dynamically stable AR-601M robot locomotion in Simulink. Int. Conf. on Mechanical, System and Control Engineering, MATEC Web of Conf., vol. 75, 09004, 2016.
- [10] R. Khusainov, I. Shimchik, I. Afanasyev, and E. Magid. Toward a human-like locomotion: Modelling dynamically stable locomotion of an anthropomorphic robot in Simulink environment. Int. Conf. on Informatics in Control, Automation and Robotics, Vol. 2, pp. 141-148, 2015.
- [11] A. Tchitchigin, M. Talanov, L. Safina, and M. Mazzara, Robot Dream. Cham: Springer Int. Publishing, 2016, pp. 291-298.
- [12] A. Tchitchigin, M. Talanov, and L. Safina, Neuromorphic robot dream, BioNanoScience, pp. 1-2, 2016.
- [13] V. Demin, V. Erokhin, A. Emelyanov, S. Battistoni, G. Baldi, S. Iannotta, P. Kashkarov, and M. Kovalchuk, Hardware elementary perceptron based on polyaniline memristive devices, Organic Electronics, vol. 25, pp. 16-20, Oct. 2015.
- [14] M. Prezioso, F. Merrikh Bayat, B. Hoskins, K. Likharev, and D. Strukov, Self-Adaptive Spike-Time-Dependent Plasticity of MetalOxide Memristors, Scientific Reports, vol. 6, p. 21-31, Feb. 2016.
- [15] K. A. Takashi Kohno, A three-variable ultralow-power analog silicon neuron circuit, 2016.
- [16] M. Sokolov, R. Lavrenov, A. Gabdullin, I. Afanasyev, and E. Magid. 3D modelling and simulation of a crawler robot in ROS/Gazebo. Int. Conf. on Control, Mechatronics and Automation, pp. 61-65, 2016.
- [17] E. Magid, T. Tsubouchi, E. Koyanagi, and T. Yoshida, Building a Search Tree for a Pilot System of a Rescue Search Robot in a Discretized Random Step Environment. J. of Robotics and Mechatronics, Vol. 23 (1), pp. 567-581, 2011.
- [18] P. Krzysteczko, J. Muenchenberger, M. Schafers, G. Reiss, and A. Thomas, The memristive magnetic tunnel junction as a nanoscopic synapse-neuron system, Adv. Mater., vol. 24, p. 762, 2012.
- [19] S. Jo, T. Chang, I. Ebong, B. Bhadviya, P. Mazumder, and W. Lu, Nanoscale memristor device as synapse in neuromorphic systems, Nano Lett., vol. 10, pp. 1297-1301, 2010.
- [20] V. Erokhin and M. Fontana, "Thin film electrochemical memristive systems for bio-inspired computation, " J. Computational Theor. Nanosci., vol. 8, pp. 313-330, 2011.
- [21] T. Berzina, S. Erokhina, P. Camorani, O. Konovalov, V. Erokhin, and M. Fontana, Electrochemical control of the conductivity in an organic memristor: A time-resolved x-ray fluorescence study of ionic drift as a function of the applied voltage, ACS Appl. Mater. Interfaces, vol. 1, pp. 2115-2118, 2009.
- [22] T. Berzina, A. Smerieri, M. Bernabo, A. Pucci, G. Ruggeri, V. Erokhin, and M. Fontana, Optimization of an organic memristor as an adaptive memory element, J. Appl. Phys., vol. 105, p. 124515, 2009.
- [23] V. Erokhin, T. Berzina, K. Gorshkov, P. Camorani, A. Pucci, L. Ricci, G. Ruggeri, R. Sigala, and A. Schuz, Stochastic hybrid 3d matrix: Learning and adaptation of electrical properties, J. Mater. Chem., vol. 22, pp. 22 881-22 887, 2012.
- [24] A. Smerieri, T. Berzina, V. Erokhin, and M. Fontana, A functional polymeric material based on hybrid electrochemically controlled junctions, Mater. Sci. Engineer. C, vol. 28, pp. 18-22.
- [25] M. A. Goodrich, and A. C. Schultz. Human-robot interaction: a survey, Foundations and trends in human-computer interaction, vol. 1 (3), 203-275, 2007.
- [26] M. Siegel, The sense-think-act paradigm revisited. IEEE Int. Workshop on Robotic Sensing, pp. 1-5, 2003.
- [27] C. Urmson, R. Simmons, and I. Nesnas, A generic framework for robotic navigation. IEEE Aerospace Conf., vol. 5, pp. 2463-2470, 2003.
- [28] T. P. Vogels, R. C. Froemke, N. Doyon, M. Gilson, J. S. Haas, R. Liu, A. Maffei, P. Miller, C. Wierenga, M. A. Woodin, F. Zenke, and H. Sprikeler, Inhibitory synaptic plasticity: spike timing-dependence and putative network function, Frontiers in Neural Circuits, vol. 7, p. 119, 2013.