



RESEARCHER PROFILE

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Google scholar KHAIRUL ANNUAR ABDULLAH

EDUCATION

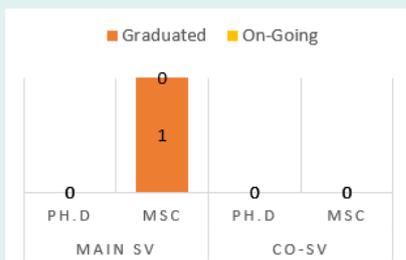


- Ph.D. (Visual Informatics), Universiti Kebangsaan Malaysia
- M.Sc. (IT-Manufacturing), Universiti Teknologi Malaysia
- B.Sc. (Computer) (Hons) with Industrial Computing major, Universiti Teknologi Malaysia

AREAS OF EXPERTISE

- Bio-inspired Computation
- Industrial Robots
- Manufacturing Systems
- Industrial Computing

SUPERVISION



COLLABORATORS



unisel
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FESTECH

TS. DR. KHAIRUL ANNUAR ABDULLAH

LECTURER

Khairul Annuar Abdullah is a Lecturer at Faculty of Computer Science and Mathematics, Universiti Malaysia Terengganu. Prior to this, Abdullah was an academician at Universiti Teknologi Malaysia and Universiti Selangor for more than 20 years. He is a Professional Technologist under Malaysia Board of Technologists.

CONTACT

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SELECTED RESEARCH PROJECTS

- ✓ Fundamental Research Grant Scheme from Ministry of Higher Education. Support Vector Machine Regression Model for Inverse Kinematic Motion Control of Automation Robotics. (2021 – 2024). RM 75,200.
- ✓ Selangor State Research Grant from Selangor State Government. Robotic Manipulator Arm Inverse Kinematic Prediction with Hybridized Nonlinear Regression – Neural Networks Model. (2018–2021). RM 45,000.
- ✓ Bestari Grant from Universiti Selangor. Predictive Model for Manipulator Arm Kinematics Based on Fusion of Neural Network and Evolutionary Algorithm. (2017–2018). RM 5,000.

SELECTED PUBLICATIONS

- ✓ **Abdullah, K.A.**, Yusof, Z., Raja Lope Ahmad, R.M.T., Abd. Rauf, M.F., Adnan, Z., Wan Hassan, W.A. & Sulaiman, R. 2022. Algebraic models based on trigonometric and Cramer's rules for computing inverse kinematics of robotic arm. International Journal of Mechatronics and Automation 9(1): 1–11. <https://doi.org/10.1504/ijma.2022.120486>. Scopus.
- ✓ **Abdullah, K.A.**, Yusof, Z. & Sulaiman, R. 2018. Spreadsheet-based neural networks modelling and simulation for training and predicting inverse kinematics of robot arm. International Journal of Computer Aided Engineering and Technology 10(3): 218–243. <https://doi.org/10.1504/ijcaet.2018.090533>. Scopus.
- ✓ **Abdullah, K.A.**, Abd. Rauf, M.F., Yusof, Z. & Sulaiman, R. 2020. Inverse kinematic manipulation control and curve trajectory tracking of robotic arm using tangential mathematical models. International Journal of Engineering Trends and Technology – Innovative Research in Computers, Automation & Technology 81–87. <https://doi.org/10.14445/22315381/cati2p213>. Scopus.
- ✓ **Abdullah, K.A.**, Marjudi, S., Yusof, Z. & Sulaiman, R. 2019. Algebraic-trigonometric nonlinear analytical inverse kinematic modeling and simulation for robotic manipulator arm motion control. Dlm. Badioze Zaman, H. et al. (pnyt.). Advances in Visual Informatics – International Visual Informatics Conference 2019 (IVIC 2019) – Lecture Notes in Computer Science, Vol. 11870, hlm.291–304. Switzerland: Springer. WoS (CPCI), Scopus.
- ✓ **Abdullah, K.A.**, Yusof, Z. & Sulaiman, R. 2015. Computational performance of iterative methods in modeling and solving linear system. Global Journal of Pure and Applied Mathematics 11(2): 715–724. Scopus.

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