Designing a Validation Method for Remote Measurements Dedicated To Investigation of Bucket Wheel Excavator Lattice Structure Internal Stress in Harsh Environment

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Abstract. The paper is a summarizing the validation stage of the strain gauges based remote measurements in bucket wheel lattice structures. The validation process is required when multiple and synchronized measurements are required in harsh environment. The authors propose virtual models with specific interaction facilities demanded in dynamic measurement systems (like FFT parameterization). The provided data from the remote measurement system (8 heads, discrete values) are processed in time and frequency for completing the range of values, for data synchronization for realistic strain distribution for proposed lattice structures. The proposed validation method is also acting for cleaning the inter-channel influences in measurements.

1. Introduction

The specific strength cutting of coal and of surface rocks, from the mine quarries, varies to great values in the mining field. For this reason, the splintering forces on the cutting teeth also have significant variations in the different mining fields. The size and direction of the forces from the cutting teeth also depends on the geometry of the teeth, their place and the direction of mounting in the bucket of the bucketed wheel [1,3].

Due to the complexity of the excavation process and of cinematic of the cutting tool, the accurately determination of the forces in the cutting teeth can be realized only through an experimental method in situ, reason for which it has been searched to conceive and to realize dynamometric teeth identical to the regular cutting teeth, which to provide a dynamometric bucket, and an electronic installation for measuring data into locations established previously and suited for it.

Because the measured information and recorded is represented by the specific displacements from the applying points of the SG onto the teeth, the relations between them and the components of the resulting points have been established for each tooth (normal, lateral, tangent) [8,9].
Figure 1. Bucket wheel excavator tooth: a) The tooth with the places where the strain gage will be placed, b) The tooth with soldered strain gage.

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2. Bucket wheel excavator stress intensity factor

The specific strength cutting of coal and of surface rocks, from the mine quarries, varies to great values in the mining field. For this reason, the splintering forces on the cutting teeth also have significant variations in the different mining fields. The size and direction of the forces from the cutting teeth also depends on the geometry of the teeth, their place and the direction of mounting in the bucket of the bucketed wheel [2,5].

2.1. Stress intensity factor considerations

To establish the program to gather and modify the data obtained from the measurements it is necessary to establish the relations between the forces $F_{x1}$, $F_{y1}$, $F_{z1}$ with random values, which act onto the dynamometric tooth in the splintering process, his geometrical parameters and the specific linear displacements. A crack intensity factor is referring to three different types of loading that cause displacements of the crack plane, tends to open the crack. The approach I is valid when the force is applied normal to the crack plane (tends to open the crack). The approach II refers to in-plane shear and causes the two crack surface to slide against each other. The approach III is valid when out-of-plane shear is applied and tends to tear the two crack surface apart.

First approach:

\[
\sigma_x = \frac{K_1}{\sqrt{2\pi r}} \cos \frac{\theta}{2} \left( 1 - \sin \frac{\theta}{2} \sin \frac{3\theta}{2} \right)
\]

\[
\sigma_y = \frac{K_2}{\sqrt{2\pi r}} \cos \frac{\theta}{2} \left( 1 - \sin \frac{\theta}{2} \sin \frac{3\theta}{2} \right)
\]

\[
\tau_{xy} = \frac{K_1}{\sqrt{2\pi r}} \sin \frac{\theta}{2} \cos \frac{\theta}{2} \cos \frac{3\theta}{2}
\]

Second approach:

\[
\sigma_x = -\frac{K_2}{\sqrt{2\pi r}} \sin \frac{\theta}{2} \left( 1 - \cos \frac{\theta}{2} \cos \frac{3\theta}{2} \right)
\]

\[
\sigma_y = \frac{K_2}{\sqrt{2\pi r}} \sin \frac{\theta}{2} \cos \frac{\theta}{2} \cos \frac{3\theta}{2}
\]
\[
\sigma_{xy} = \frac{K_2}{\sqrt{2\pi r}} \cos \theta \left( 1 - \frac{\sin \theta}{2} - \frac{3\theta}{2} \right)
\]  

(2)

This last approach of deformation called out-of-plane shear mode, does not occur in the plane elastic problem. The stress intensity factors for all three types of approaches are denoted as \(K_1\), \(K_2\) and \(K_3\).

The parameters \(\tau_{xy} = \tau_{yz} = 0\) for plane stress and plane strain. The parameters \(\sigma_z = 0\) for plane stress and \(\sigma_z = (\sigma_x + \sigma_y)/2\) for plane strain [4].

**Third approach:**

\[
\begin{align*}
\sigma_{xz} &= \frac{K_{m}}{\sqrt{2\pi r}} \sin \theta/2 \\
\sigma_{yz} &= \frac{K_{m}}{\sqrt{2\pi r}} \cos \theta/2
\end{align*}
\]  

(3)

**Figure 2.** Deformation of the crack for bucket wheel excavator tooth.

**Figure 3.** Dynamometric bucket mounted onto RS 1300 type excavators.
According to figure 3 the specific deformations the forces $F_{x1}$, $F_{y1}$, $F_{z1}$, applied to the center of the edge of the tooth and the geometrical characteristics of the section, the following relations are obtained [6,8]:

$$
E \cdot \varepsilon_1 = F_{x1}\left(-\frac{1}{A} + \frac{e_1 \cdot y_1}{I_z}\right) + F_{y1} \frac{l \cdot y_1}{I_z} - F_{z1} \frac{l \cdot z_1}{I_y}
$$

$$
E \cdot \varepsilon_2 = F_{x1}\left(-\frac{1}{A} + \frac{e_1 \cdot y_1}{I_z}\right) + F_{y1} \frac{l \cdot y_2}{I_z} - F_{z1} \frac{l \cdot z_2}{I_y}
$$

$$
E \cdot \varepsilon_3 = -F_{x1}\left(\frac{1}{A} + \frac{e_2 \cdot z_3}{I_y}\right) + F_{y1} \frac{l \cdot y_3}{I_z} - F_{z1} \frac{l \cdot z_3}{I_y}
$$

From the solving of the equations system it yields:

$$
F_{x1} = E \frac{\varepsilon_2 y_3 - \varepsilon_3 y_2}{\varepsilon_2} - \frac{(\varepsilon_1 - \varepsilon_2) \left(\varepsilon_2 y_3 - \varepsilon_3 y_2\right)}{y_3 - \frac{1}{A} + \frac{e_1 y_1}{I_z}} + y_2 \left(\frac{1}{A} + \frac{e_2 z_3}{I_y}\right)
$$

$$
F_{y1} = EI_2 \frac{\varepsilon_2}{y_3 - \frac{1}{A} + \frac{e_1 y_1}{I_z}} - \frac{\left(\varepsilon_2 y_3 - \varepsilon_3 y_2\right)}{y_3 - \frac{1}{A} + \frac{e_1 y_1}{I_z}} + y_2 \left(\frac{1}{A} + \frac{e_2 z_3}{I_y}\right)
$$

$$
F_{z1} = EI_y \frac{\varepsilon_1 - \varepsilon_2}{z_2 - z_1}
$$

With these values the upper relations become:

$$
F_{x1} = 3020 \cdot 10^4 \left(-39,4584 \varepsilon_1 + 39,6684 \varepsilon_2 - 35,21 \varepsilon_3\right)
$$

$$
F_{y1} = 5683 \cdot 10^4 \left(8,7668 \varepsilon_1 + 1,2396 \varepsilon_2 - 1,3072 \varepsilon_3\right)
$$

$$
F_{z1} = 6109 \cdot 10^4 \left(\varepsilon_1 - \varepsilon_2\right)
$$

It is specified that between the forces $F_{x1}$, $F_{y1}$, $F_{z1}$ and the forces on the tooth resulted from the cinematic of the working tool, the forces $F_x$, $F_y$ (tangent and normal to the trajectory resulted from the rotating movement of the bucketed wheel) and $F_z$ (resulted from the horizontal tipping of the bucketed wheel by the excavator arm for cutting radial) there are the following relations:
\[
\begin{align*}
F_{x1} &= -F_y \sin 52^\circ + F_x \sin 38^\circ \\
F_{y1} &= F_x \cos 38^\circ + F_y \cos 52^\circ \\
F_{z1} &= F_z
\end{align*}
\] (7)

2.1.1. Hardware implementation

The bucket wheel excavator lattice structure internal stress is measured with the developed programmable system.

**Figure 4.** Remote measurements system for investigation of bucket wheel excavator.

**Figure 5.** Testing measuring module based on Teensy microcontroller.
The nRF24L01 module is an RF module that works on the 2.4 GHz band and is perfect for wireless communication in an industrial application because it will penetrate even thick concrete walls. The nRF24L01 has a function to automatically check if the transmitted data is received at the other end. There are a couple of different versions of the NRF-family chips and they all seem to work in a similar way. These modules has an impressive range, with some versions that manages up to 1000 m (free sight) communication and up to 2000 m with a bi-quad antenna.

2.1.2. Software implementation

To start working with the Teensy, all you need to do is plug in your USB cable to your computer and your Teensy board. There are two options for programming the Teensy boards - your favorite C compiler or the Arduino IDE.

```c
#include <SPI.h>
#include <RF24.h>
#include "RF24.h"
#include <Wire.h>

// RF24 code
RF24 radio(3, 19); //initializing RF24

byte addressed[16] = {"0"};

#define cs 10 //RF24 -> cs
#define cs 6 //microSD -> cs

const int MPU_addr=0x68;

// nRF24

void setup() {
  pinMode(cs, OUTPUT);
  pinMode(sck, OUTPUT);
  pinMode(sclk, OUTPUT);

  Wire.begin();
  Wire.beginTransmission(MPU_addr);
  Wire.write(0x06); // IDENTITY register
  Wire.write(0);
  Wire.endTransmission(true);

  Serial.begin(9600);
  Serial.print("CLEAN_DATA");
  Serial.println("LABEL, WR_CIT,T1,T2,T3,T4,ACX,ACY,ACZ,GYX,GYZ,Temp Micros");
}
```
void setup ()
{
    pinMode(cs, OUTPUT);
    pinMode(sen, OUTPUT);
    pinMode(2, OUTPUT);

    Wire.begin();
    Wire.beginTransmission(MPU_addr);
    Wire.write(0x3B); // Register #1  (ACC_XOUT_H)
    Wire.write(0);
    Wire.endTransmission(true);

    Serial.begin(9600);
    Serial.print("C:\\Windows NT\\bin\\CLEANDATA\"");
    Serial.println(""/LABEL, NR_ort,T1,T2,T3,T4,AcX,AcY,AcZ,GyX,GyY,GyZ,Tempr micros"");

    Serial.println("INITIALIZING 3D CARD..."); // Verifying SD card
    delay(300);
    if ( !SD.begin(cs) )
        Serial.println("SD CARD NOT DETECTED :();
    else
        Serial.println("SD CARD READY FOR WRITING :();


datafile = SD.open("data.csv", FILE_WRITE); // writing data_file to SD card

void loop ()
{
    Wire.beginTransmission(MPU_addr);
    Wire.write(0x3B); // starting with register 0x3B (ACC_XOUT_H)
    Wire.endTransmission(true); // request a total of 14 registers

    AcX=Wire.read()<<8|Wire.read(); // 0x3B (ACC_XOUT_H) & 0x3C (ACC_XOUT_L)
    AcY=Wire.read()<<8|Wire.read(); // 0x3D (ACC_YOUT_H) & 0x3E (ACC_YOUT_L)
    AcZ=Wire.read()<<8|Wire.read(); // 0x3F (ACC_ZOUT_H) & 0x40 (ACC_ZOUT_L)
    Tmp=Wire.read()<<8|Wire.read(); // 0x41 (TEMP_OUT_H) & 0x42 (TEMP_OUT_L)
    GyX=Wire.read()<<8|Wire.read(); // 0x43 (GYRO_XOUT_H) & 0x44 (GYRO_XOUT_L)
    GyY=Wire.read()<<8|Wire.read(); // 0x45 (GYRO_YOUT_H) & 0x46 (GYRO_YOUT_L)
    GyZ=Wire.read()<<8|Wire.read(); // 0x47 (GYRO_ZOUT_H) & 0x48 (GYRO_ZOUT_L)
    Temp=Tmp/340.00+36.53; // equation for temperature in degrees C from datasheet
    T1=scale1.get_units(10);
    T2=scale2.get_units(10);
    T3=scale3.get_units(10);
    T4=scale4.get_units(10);

    Monitoring and processing system of mechanical effort with high performance microcontroller is
done with the aid of weight sensors which are connected to a data acquisition board. The objective of
this project is to create an smart electronic weighing system programmed by MC, this device has
capacity to specify the measured weight, weight differences over time and weight thresholds. Data taken from these input devices will be transmitted with an antenna, via wireless, can be stored on a card or can be read directly. Weighing sensors or tensometric stamps reprocessed by an HX711 instrumentation module. In the case of the weight sensor reading module this must be programmed, programming is done on Serial and can be done with an Arduino programmed as a programmer.

3. Results and discussions
The virtual mechanical strain bridge instrument consists on the Data acquisition module presented previously, connected to the Personal computer, the needed software for hardware functioning (Windows XP and the application strain bridge instrument program, developed with Keysight VEE Pro software).

![Figure 6. Measuring module configuration.](image6.png)

![Figure 7. The graphical panel of the virtual mechanical stress measurements.](image7.png)
The software solution for the virtual bridge instrument was developed using the Visual Programming Environment for Data Acquisition, HP VEE and Matlab Script, Hewlett Packard. Using the MatlabScript software, each bridge equation was specifically expressed and a graphical program was developed (figure 7). The main instruments are the acquisition data where the values from the measuring module. Using the magnitude spectrum graphical instrument the frequency of the signals are displayed (like FFT parameterization).

Figure 8. Spectral FFR analysis.

Based on the results of such measurements performed by the statistical processing, the relevant characteristics have led to the mechanical cutting of lignite.

4. Conclusions
The results of research performed regarding the cutting tools of the bucket wheel excavators; in order to reduce the energy consumption and the teeth wear during the lignite and overburden rock are presented.

On the basis of the methodology of analytical determination of force and energetic characteristics, starting from the results of experimental results in laboratory and taking into account the technical characteristics of the excavators

It has also been established that the dynamometric tooth to have the same geometrical parameters and to work in the same conditions as the real teeth. Following the analysis of the bucketed wheels and the way that the teeth is fixed into the holders it has resulted that the strain gage should be placed onto the tail of the tooth, in the free area between the tooth’s shoulder and it’s holder, in places covered with metallic plates to protect from mechanical hits, and environmental factors.

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**Acknowledgments**

The paper is based on research activity that is the subject of the invention: Installation for in-situ measuring and recording the forces acting upon the teeth of the cutting element in rock shattering machines, Patent number RO 123483 B1.

The paper is a part of an European Union research project founded by the Coal and Steel Founding, RFCS agreement No. RFCR-CT-2015-00003 (BEWEXMIN)