Curved rotary module for modular construction of motion structures

Jozef Svetlík (SK) jozef.svetlik@tuke.sk
Peter Demeč (SK) peter.demec@tuke.sk

BIOGRAPHICAL NOTES

Jozef Svetlík, Ing. PhD. (born in 1977) assistant professor at the Department of Manufacturing Engineering and Robotics (since 2003) at the Faculty of Mechanical Engineering in TU Košice (SjF, TUKE). Graduate TUKE SjF 2000, scientific degree of Doctor of Philosophy (PhD) defended at Technical University of Košice in 2004. Internal PhD. student SjF TUKE (2000-2003). Member of the editorial board of “Journal of Applied Statistics”. Research interests of construction machinery and modular robotics. Co-author of the script “modules for the construction of production machinery” and “Robotics - Technical equipment for automated workplaces: inter-operational handling. Winner of “Siemens Excellence Award 2004” for the dissertation. The holder of an honorary recognition of the International Engineering Fair 2003 in Nitra Agrokplex for “Intelligent modular assembly system”. Team member “SjF Tupe robotics”, which is several times European champion and world champion from 2010 in robotic soccer. Author of a utility model “rotary module for modular construction machinery” and patent “contactless transmission of electrical power for modular machines” (in the approval process). Author of over 60 scientific and professional articles in journals and contributions to scientific and professional conferences.

Peter Demeč, prof. Ing. PhD. (born in 1952) professor of Production machinery and equipment (since 2003) at the Faculty of Mechanical Engineering TU of Košice (SjF, TUKE). Graduate SjF TUKE in 1975, scientific degree Candidate of Sciences (CSc / PhD) defended the STU in Bratislava in 1984, Associate Professor of habilitated SjF TUKE 1994. SjF TUKE prodean (1993-1996), Head of Department of Manufacturing Technology (1997-2002), Deputy Head of the Department of Production Systems and Robotics (2003-present). Member of scientific advice SjF TUKE, Faculty of Environmental and Manufacturing Technology University in Zvolen, Faculty of Special Technology and University of Alexander Dubček in Trenčín, a member of the Society for machine tools, the Czech Republic, Club President of the Slovak Association of Mechanical Engineers for SjF TUKE, Member of Editorial Board, and MM Science Journal Technologist. Research interests of construction, virtual prototyping, and precision machine tools. Author of the memoir „The accuracy of machine tools and its mathematical modeling“ (Košice: Vienala 2001) and over 130 scientific and professional articles in journals and contributions to scientific and professional conferences.

KEY WORDS

Modular Machine, Rotation Module, Robotic Manipulator, Curved Rotary Module, Modular Construction, Robot Workspace, Serial Robot

ABSTRACT

The article deals with the mechanics of modular machines and examines in detail the parameters of the principle of joining newly designed curved rotary modules into
homogeneous serial kinematical chain with five degrees of freedom of movement. The result of analysis is generated workspace built on the basis of 60° curved rotary module with unlimited rotation for a serial kinematical structure with homogeneous 5DOF.

INTRODUCTION
The idea of modular principle of machines is not new [6]. In the past there have been many creative and innovative ideas from which the amount of time is transformed into a real functioning machine. In the field of motion structures with modular serial construction, there are some innovative solutions to many well-known and unknown companies, for example: SCHUNK, Epson, Yamaha. These concepts give a chance to build machines for the handling, processing and other tasks as seen in Fig. 1.

Known modular systems also offer a range of modular motion units. These modules are characterized by different attributes, parameters and sizes. Modules can be translational, rotational, and other rare cases. The main weaknesses of these modules include the limitation of rotational movement and greater complexity of design. From these facts suggest limiting it to the prescribed limits of the range of motion (rotation in the range max. 270 degrees, translational motion in the range of 350 mm, and so on). The resulting movement possibilities of cinematic chain composed of these modules have a limited range of rotational movement. This eliminates the shortcomings hereinafter referred rotation module for the construction of modular machines.

1 Principle of Design Solutions
Rotation module, designed for modular construction machinery, allows merge these modules and the creation of kinematic chain with theory of any number of degrees of freedom of movement, able to perform controlled motion [1]. Its internal structure consists of a body, interlink and clamping plate, which performs a rotational movement over the body, as seen in Figs. 2, 3. In the body of a rotary module is stored servomotor and reducer. Servomotor is equipped with incremental encoder and an electromagnetic brake.

Clamping plate of rotation module is attached to the body through a rotary motion tie of one degree of freedom of movement and it is located on the clamping mechanism for connecting interlink...
to the next module (modules in the chain). This rotary motion linkage is unlimited range of motion [11]. Interlink of rotation module is geometrically curved and includes a bayonet fixing mechanism for connecting of clamping plate of the previous module (modules in the chain). Angle of curvature determines the scope and characteristics of the working space of the modular machine assembled from these modules.

Homogeneous kinematic structure of a modular concept consists of several identical or identical type (eg. size or curvature of the diverging) rotary motion modules [12].

Example of 3D display modular manipulator with 6 degrees of freedom of movement is shown in Fig. 5, when is used the extension part [9]. This part serves to increase the reach of kinematic chain and has no internal drive system. It is inserted between the modules and in this way, adjusts the characteristics of the working space and also reachability positioning member in the end of it. Except the extension member are also used rotating different modules with varying degrees of curvature. This method achieves a high flexibility and variability of working space and reachability of location is a function of mutual selection and arrangement of appropriate modules and extension parts.

Links between all internal parts of the module and also between the individual modules are fixed (except rotary links between the body and clamping plate), sufficiently rigid and unable to pass the required mechanical load. Communication equipment intended for control are proposed as a wireless, eg.: WiFi, Bluetooth and so on. Electronic communications modules with accessories should be positioned into the body of the module. Connection of individual modules should be realize in terms of flexibility by bayonet method.

Example of 3D display modular manipulator with 6 degrees of freedom of movement is shown in Fig. 4, which are used to build basic rotary modules. This series homogenous structure is characterized by its simplicity and not the most appropriate reachability within your workspace. To achieve the desired position to be extensive rotationing of many modules, which is relatively energy consuming.

![Fig. 3 Modification of 3D models of a separate rotary module of varying degrees of curvature](image1)

![Fig. 4 3D model of the modular machine, assembled from rotary motional basic modules, with 6 degrees of freedom of movement](image2)

![Fig. 5 3D model with a modular machine using an extension part and adapted the basic modules with 6DOF](image3)
2 Mathematical Description of Structure

For the mathematical description of a serial kinematic chain is best to use Denavit-Hartenberg principle of deployment of joint chain to the coordinate systems [2]. This deployment will achieve particulate transformation matrices (1). This transformation matrix “Ab0” describes the position and rotation of the first couple coordinate systems, thus the current position of the base “b” and the first module “0” in Fig. 6, where q1 and q5 are common variables. In our case, the steering angles of rotary modules are within the interval (0, 2π). Variables lx1 and lx2 represent distance of local coordinate systems according to the principle of D-H principle. Variable “a” represent the angle of curvature of the module used in this case was used 60° angle. Further transformation matrices in order of the other members of the kinematic chain are analogous to the shape and functions are gradually variables q2 and q5. In order to get the overall transformation matrix is necessary transformation matrix between neighboring coordinate system multiplied “Ab0” and “A01”, resulting in a total transformation matrix of great complexity. Relationship (2) reflects the partial transformation matrix between the base “b” and the second movable member in order-rotating module, “1”. After multiplying all the sub-transformation matrices of type “A” there

\[
A_{b0}(q_1, q_2, q_3, q_4, q_5) = \begin{pmatrix}
\cos q_1 & -\sin q_1 \cos a & \sin q_1 \sin a & l_{x1} \cos q_1 \\
\sin q_1 & \cos q_1 \cos a & -\cos q_1 \sin a & l_{x1} \sin q_1 \\
0 & \sin a & \cos a & 1 \\
0 & 0 & 0 & 1
\end{pmatrix}
\]

(1)

\[
T_{10}(q_1, q_2, q_3, q_4, q_5) = A_{b0}(q_1, q_2, q_3, q_4, q_5).A_{01}(q_1, q_2, q_3, q_4, q_5) = \\
\begin{pmatrix}
3 \cos q_1 & \cos(q_2 + q_3) & \sqrt{2} \cos q_2 & \sqrt{2} \cos q_2 & \sqrt{2} \cos q_2 \\
3 \sin q_1 & \sin(q_2 + q_3) & \sqrt{2} \sin q_2 & \sqrt{2} \sin q_2 & \sqrt{2} \sin q_2 \\
\frac{\cos q_1}{\sqrt{2}} & \frac{\sin q_1}{\sqrt{2}} & \frac{\sin q_2}{\sqrt{2}} & \frac{\sin q_2}{\sqrt{2}} & \frac{\sin q_2}{\sqrt{2}} \\
\frac{\cos q_1}{\sqrt{2}} & \frac{\sin q_1}{\sqrt{2}} & \frac{\sin q_2}{\sqrt{2}} & \frac{\sin q_2}{\sqrt{2}} & \frac{\sin q_2}{\sqrt{2}} \\
\frac{\cos q_1}{\sqrt{2}} & \frac{\sin q_1}{\sqrt{2}} & \frac{\sin q_2}{\sqrt{2}} & \frac{\sin q_2}{\sqrt{2}} & \frac{\sin q_2}{\sqrt{2}}
\end{pmatrix}
\]

(2)

3 Identification of Workspace

To identify the shape and scope of workspace was necessary to define transformation matrices in a MathCAD program [3, 8] and also define the geometrical parameters: the curvature module a=π/3 rad, module length l1=100 mm, width module l2=100 mm. The distance between the coordinate system is defined as a variable lx1 and lx2 (3, 4). It is necessary to define the scope of the local variable q1...q5 is from the interval (0, 2π) and the step number is π/6 rad.
Formularization of the overall transformation matrix and the gradual substitution of the general variables $q_1$ until $q_5$ the specified steps to get around 33000 points. These points represent the final position in the end coordinate system rotating module. Their display in a suitably chosen Cartesian coordinate system we will likely shape, size and scope of workspace. Workspace of homogeneous serial kinematic structure of Fig. 6 is reproduced in Fig. 7.

### 4 Conclusion

The overall result of the described technical solution is a modular system for the building of modular machines assembled from identical or identical type (eg diverging of size or curvature) rotary motion units with unlimited rotation range of motion [7]. It is necessary to make more extensive analysis and find the best angle of curvature of the building module. This angle should provide for widest possible range of workspace and also a good reachability of desired point in this workspace. On the other side should be provide the safe operation of that in any position of the kinematic chain can happen to self-collision kinematic structure [4]. It is probable that the varying degree of freedom of movement should always choose a different angle of curvature of the basic module [5]. Similarly it is probable that application-specific angle of curvature may be appropriate basic module other than that which is derived simulation in virtual terms [10,13].

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