The Study of Motion Analysis and Control Principle of Three-DOF Turnover Wall

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Abstract—A three-DOF (degree of freedom) parallel mechanism is designed and integrated with the moveable wall which the solar photovoltaic panels are installed on it. In order to control the spatial posture of the wall, geometric analysis was used to get the kinematic inverse solution and the kinematic positive solution of the mechanism, to obtain the relationship among push distance, rotation angle and flip angle. MATLAB was used to get numerical solution and show the relationship of them intuitively. The motor control program was designed and optimized through feedback structure. The motor could be controlled according to the deviation. Result indicates the wall can be controlled more accurately according to the change of solar angle and gets the maximal generating efficiency.

Keywords—prefabricated building; parallel mechanism; positive and inversion solution analysis; solar energy

I. INTRODUCTION

Parallel mechanism is widely used because of the good dynamic performance [1]. It can be found in many applications, such as airplane simulators, adjustable articulated trusses and mining machines. J. Wang et al [2] derived the velocity equations and the singularity loci of the three types of kinematically redundant parallel mechanisms they proposed. It should be acknowledged that the kinematically redundant mechanisms have improved performance over non-redundant ones [3,4]. Moreover, O. Altuzarra et al. have been researching on parallel continuum mechanisms. They did quasistatic analysis [5,6], used numerical direct integration to looking for possible solutions, and then made use of particular conditions on a certain mechanism to find systematically all solutions [7,8]. As for the control of the mechanisms, cable-driven parallel mechanisms are widely used [9,10,11], however, the interference between cables that may occur during movement [12,13].

In order to make full use of building space and solar energy in prefabricated building, a new parallel mechanism is designed and solar photovoltaic panels are installed on the moveable wall. By changing the spatial posture of the wall the objective can be achieved. In this paper, the structure is disussed. The kinematic positive and inverse solution is analyzed, the relationship between the push distance of the electric push rods and space angle is gotten. MATLAB is used to carry out simulation analysis. Control strategy is designed to achieve more accurate control.
STRUCTURAL DIAGRAM OF MECHANISM (1- FIXED WALL; 2- THE FIRST ELECTRIC PUSH ROD FIXING DEVICE; 3- THE FIRST ELECTRIC PUSH ROD; 4- FISH EYEBALL UNIVERSAL JOINT WITH LOCATING PIN; 5- FLIPPED OUTER WALL; 6- SOLAR PHOTOVOLTAIC PANEL; 7- THE SECOND ELECTRIC PUSH ROD STORAGE BOX; 8- THE SECOND ELECTRIC PUSH ROD; 9- FISH EYEBALL UNIVERSAL JOINT WITHOUT LOCATING PIN; 10- THE SLIDER; 11- THE SECONDARY SLIPPERY COURSE; 12- THE PRIOR SLIPPERY COURSE; 13- SLIDE RAIL ELECTRIC PUSH ROD)

Structural diagram of this mechanism structure is shown in Figure I(c), the calculation formula of single closed loop of space mechanism is used to get its degrees of freedom:

\[ M = (6 - m)n - \sum_{k=m+1}^{n} (k - m)P_k = 3 \]  \hspace{1cm} (1)

In this formula, \( m \) represents the number of common constraint, \( n \) represents the number of component, \( k \) represents the constraint number of kinematic pair of level \( k \), \( P_k \) represents the number of kinematic pair of level \( k \).

From the analysis above, the wall has three degrees of freedom, namely, one degree of freedom to move along the X-axis and two degrees of freedom to rotate around \( A_2 \) points parallel to the z-axis and \( A_2P \) axis.

In the process of posture adjustment, the electric push rod receives the operation command and by adjusting the push distance, the wall can reach the required posture. For the convenience of research, the movement process is divided into three steps:

The first step is to achieve the non-interference posture. The first electric push rod motor controls the extension of the push rod outwards to make the upside of the outer wall do not interfere with the wall during the period from moving horizontally out to the flip process. The second step is to get the retroflex posture based on the first step. The two second electric push rods coordinate synchronously so that the wall takes the horizontal straight line where the first electric push rod connects the hinge point \( A_2 \) to the wall as the axis, and flips upward to the desired angle, at which point the outer wall takes an angle of timestamp to rearrange itself in the YOZ plane. The third step is to reach the rotating posture. Based on the retroflex posture and according to the solar elevation angles, motors control the two second electric push rods and makes the push distance of them different, thus the wall rotates to the demand angle of \( \varphi \) along the \( A_2P \) axis. If the demand of \( \theta \) and \( \varphi \) changes, then the two second electric push rods adjust the push distance according to the new requirements to achieve the new order of posture; If the outer wall needs to be closed, the push distance of the three electric push rods shall be controlled to zero to reach the closed state. According to the method of calculation of Pan F[14], we defined the solar elevation angles so that the design scope of work space of the wall can be achieved theoretically at \( \theta: (0^\circ) - (81^\circ) \), \( \varphi: (-45^\circ) - (+45^\circ) \).

The global coordinate system o-xyz was established at point O, where the hinge points installed on the ground by the two second electric push rods are \( B_{11} \) and \( B_{12} \) respectively, and the hinge points connected with the wall were \( B_{21} \) and \( B_{22} \) respectively. The projection length of the line \( B_{21}B_{22} \) on the z-axis is \( 2d \), and the perpendicular line from \( A_2 \) to the line \( B_{21}B_{22} \) was made, and the vertical foot is \( P \). The hinge point of the first electric push rod is \( A_1 \), the hinge point connecting with the wall is \( A_2 \), and the initial installation length of the three electric push rods are all \( S_0 \).

Analysis of kinematic inverse solution

Based on the analysis above, when analysis the first step of flip, the wall rotates along the horizontal axis of the hinge point \( A_2 \). The two second electric push rods synchronously push out during the rotation, so in this step, the model is simplified to the XOY two-dimensional projection plane to analyze. In Figure III, a is the distance from \( B_1 \) to the wall, \( b \) is the distance from \( A_1 \) to the bottom, \( c \) is the length of \( A_2B_2 \), the push distance of the first electric push rod is \( S_{1t} \), the push distance of the two second electric push rods with two coupling motions is \( S_{2t1} \) and \( S_{2t2} \), and the total length is \( S_t \).

![FIGURE II. FLIP STATE DIAGRAM](image)

![FIGURE III. XOY two-dimensional projection plane](image)
After reaching the required reversal angle, the second step of wall movement is studied, which is analyzing the relationship between the push distance of two second electric push rods and the rotation angle of the wall. In the process of rotation, the wall rotation along the $A_2P$ axis in Figure IV is controlled by adjusting the difference of push distance between the two rods. By analyzing the two rotational states, Figure V can be obtained according to the direction of projection. Two hinge points of the two second electric push rods connected to the wall change into $B_{21}'$, $B_{22}'$ from $B_{21}$, $B_{22}$.

The relationship between the push distance of the three push electric rods and the posture angle $\theta$ is:

$$\theta = \arctan \left( \frac{-a^2 - b^2 - c^2 - S_2^2 - S_{t1}^2}{2(a^2 + b^2 + b^2 + S_{t2}^2)} \right)$$

while

$$A = \left( a^2 + 2aS_{t1} + b^2 - c^2 - 2cS_x - S_x^2 + S_{t1}^2 \right)$$
$$B = \left( a^2 + 2aS_{t1} + b^2 - c^2 + 2cS_x - S_x^2 + S_{t2}^2 \right)$$
$$C = \left( -bc^2 + bS_x^2 + bS_{t1}^2 + b^3 + 2abS_{t2} \right)$$

According to this, controlling the angle of the wall's retroflex posture according to the requirements can be realized accurately by controlling the push distance of electric push rods in order to finish the first step of wall movement. During the rotating, let's set the solution for $x$ and $y$ to be $X_1$ and $Y_1$ respectively. Wall initial position on the projective plane is $B_{21}B_{22}$, after rotation is $B_{21}'B_{22}'$, $B_{21}B_{22}$ is always going to be 2d on the z-axis, through projection and vector relationships, the final formulas of kinematic positive solution can be expressed as:

$$\phi = \arctan \left( \frac{\sqrt{S_{t2} - S_2^2 - S_{t2}^2}}{d} \cos (\theta - \arctan \left( \frac{Y_1}{X_1} \right)) \right)$$

### III. EXPERIMENTAL SIMULATION ANALYSIS OF TURNOVER WALL

The relationship between the push distance of the second electric rod and the posture size

The spatial pose of the turnover wall is related to the size parameters, shape and installation position of the mechanism, which can reflect the mapping relationship between the posture of the end of the rods and the push distance of them. By analyzing a branched chain constraint of parallel mechanism, the relationship between the constraint and the pose angle can be obtained.

The relationship between the push distance and the angle of the second electric rod in turnover and recyclable building structure can be described as a three-dimensional space of which the boundary is $Q(S_{t2}, 0, \phi) = 0$. The distance between $B_1$ and the wall is $a=1m$, $A_1$ is 2.8m away from the base and $A_2B_2$ which is defined as $c$ is 2m. The initial installation length of the three electric rods are all $S_0=1m$, the push distance of the first push rod is $S_{t1}=1m$, the push distance of the two second electric rods with coupling motions is $S_{t2}$ and $S_{t3}$, respectively. According to the given parameter conditions and constraints, the corresponding program was written in MATLAB, and the relationship in Figure VI is obtained.
By analyzed Figure VI we can know that controlling the push distance of the second electric rod can accurately control the movable wall to the certain spatial pose. What’s more, when given an angle of $\theta$ or $\varphi$, the push distance of the second electric push rod, which controls the movement of the turnover wall, $S_{t2}$, meets the nonlinear relation with the other angle.

When the rotation angle is zero, the push distance of the two second electric rods are different. As shown in Figure VI, under the control of motors having the same speed, the push distance of the two second electric rods $S_t$ increases synchronously as their flip angle increases. When the flip angle is a constant, with the change of rotation angle, the push distance $S_t$ of the two rods increases or decreases respectively at the same speed under the control of motors having the same speed. When the flip angle and rotation angle both change, the two motors control the electric rods at different speeds or turns, so that the push distance $S_t$ of the two second electric push rods respectively reach the required value.

Analysis of the process of changing the spatial pose

After analyzing the relationship between the push distance of the second electric rod and the posture angle, we want to study the relationship between push distance $S_{t2}$, $S_{t3}$ and flip angle $\varphi$. In Figure VI, when $\varphi = 0^\circ$, we study the cross section of $S_{t2} \theta$ and the relationship is shown in Figure VII, which expresses the relationship between the demand flip angle and the push distance when the rotation angle is $\theta$.

When study the relationship between the push distance $S_t$ and the rotation angle $\varphi$. The range of $\varphi$ is $-45^\circ$~$45^\circ$. In Figure VI, when $\theta = 60^\circ$, we study the cross section of $S_{t} \varphi$ and the relationship is shown in Figure VIII which expresses the relationship between the demand rotation angle and the push distance when the flip angle is $60^\circ$.

**IV. CONTROL OPTIMIZATION**

The motor is controlled by closed-loop control, that is, deviation control. By analyzing the kinematic relationship between the components and using Laplace transform, the structure block diagram of the controller is shown in Figure IX(a). Based on this, we increase the accuracy of motor control by adding feedback structure to the angular displacement of the transmission shaft, as shown in Figure IX(b). In Figure IX(c) we consider the effects of external load torque, friction torque, gravity torque and centripetal force. The combination of feedback control and external disturbance control makes the control more accurate.

**V. SUMMARY**

Using geometric analysis to analyze kinematic inverse solution and kinematic positive solution of turnover and recyclable building construction. By controlling the push distance of the electric push rod, two angles which can express the posture of the moving wall can be accurately controlled. Through the feedback structure of deviation control, the motor can accurately control the push rod to reach the predetermined
position to receive solar energy. The energy absorbed by solar panels mounted on the turnover wall can be used to power the equipment in the building, thus enhance the utilization of solar energy.

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