

Lecture 03

More Robot Applications & Fundamentals

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Review of Lecture 2 (Feb. 01, 2020)

- **Robot Applications**
 - Industrial like Welding, Assembling, Palletizing
- **Classification of Serial Robots**
 - Coordinate system (Cartesian, etc.), Control (Servo, etc.) ...

Outline

- **More Industrial applications**
- **Students Robotics at IIT Delhi**
- **Mathematical fundamentals**
- **Summary**

PCB Assembly

- SCARA: *Selective-Compliance-Assembly Robot-Arm*
- Can assemble in vertical motion
- 4-DOF robot
 - Pick up parts located on horizontal plane
 - Bring them to assembly location
 - Orient them, and
 - Insert them in a vertical motion

Machining

- Drilling

- Robots can drill using template hole with a chamfered guide
- Gripper holds portable pneumatic drill
- It is PTP operation → manual teaching

- Deburring

- Burrs are generated in machining of metal parts
- Removal of burrs is expensive

- Two basic ways to deburr using robots
- For lightweight, it is picked up by robot and brought to deburring tool
- For heavy, the robot holds the tools
- In both, relative motion bet. tool and part is CP with high repeatability (app. 0.2 mm)

Medical

- Used in surgery (e.g., da Vinci)
- Goal: Not to replace surgeons but to assist
- Provide surgeons with a new set of versatile tools that extend his or her ability to treat patients
- Medical robotic systems are *surgical assistants* that work cooperatively with surgeons
- SS Innovations

Space

- Explorations of planets, moons, and near bodies in space
- Benefits: Lower cost and without endangering human life
- Such robots must be versatile and robust
- A space robot should have
 - Compactness and Lightness
 - Robustness
 - Versatility and Adaptability

Mining and Underwater

- Mining: To enhance productivity
 - Access unworkable mineral seams
 - Reduce human exposure to dust, noise, gas, water
- Underwater Applications
 - Prospect for minerals on the floor of the ocean
 - Salvaging of sunken vessels
 - Repair of ships
 - Sewage cleaning

Defence

- Air force, navy, and army are interested
- Applications
 - Surveillance
 - Security guard in power plants, oil refineries, and other large civilian facilities

Few Fundamentals

- **Mathematical Fundamentals**
 - Vectors and matrices
- **Manipulator**
 - Links
 - Joints
- **Degrees of freedom**
 - Definition
 - Formula

Vectors

- Array of n-numbers written column-wise (not row-wise)

$$\mathbf{a} \equiv \begin{bmatrix} a_1 \\ \vdots \\ a_n \end{bmatrix}$$

- If a row-vector is needed, use transpose

$$\begin{bmatrix} a_1, & \cdots, & a_n \end{bmatrix} \equiv \mathbf{a}^T$$

Length and Direction

- Length or magnitude or norm of a vector

$$a = \sqrt{\mathbf{a}^T \mathbf{a}} = \sqrt{a_1^2 + \cdots + a_n^2}$$

- For a Cartesian position vector, length

$$a = \sqrt{\mathbf{a}^T \mathbf{a}} = \sqrt{a_1^2 + a_2^2 + a_3^2}$$

- Direction (e.g., *Angle with XY plane*)

$$\text{Angle} = a \tan^{-1} \left(\frac{a_3}{\sqrt{a_1^2 + a_2^2}} \right)$$

Unit Vector

- A vector divided by its lengths, $\bar{\mathbf{a}} = \frac{\mathbf{a}}{a}$
- Examples of unit vectors

$$\mathbf{i} \equiv \begin{bmatrix} 1 \\ 0 \\ 0 \end{bmatrix} \quad \mathbf{j} \equiv \begin{bmatrix} 0 \\ 1 \\ 0 \end{bmatrix} \quad \mathbf{k} \equiv \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix}$$

- Any vector can be represented as

$$\mathbf{a} = a_1 \mathbf{i} + a_2 \mathbf{j} + a_3 \mathbf{k}$$

Scalar and Dot Products



- Meaning projections

$$\mathbf{a} \cdot \mathbf{b} \equiv \mathbf{a}^T \mathbf{b} = ab \cos \theta$$

$$(\mathbf{a}^T \mathbf{b} = \mathbf{b}^T \mathbf{a})$$

- Alternate way of calculations

$$\mathbf{a}^T \mathbf{b} = a_1 b_1 + \cdots + a_n b_n$$

Vector- or Cross-product

- Definition

$$\mathbf{c} = \mathbf{a} \times \mathbf{b} = \begin{vmatrix} \mathbf{i} & \mathbf{j} & \mathbf{k} \\ a_1 & a_2 & a_3 \\ b_1 & b_2 & b_3 \end{vmatrix}$$

$$\mathbf{c} = (a_2b_3 - a_3b_2)\mathbf{i} + (a_3b_1 - a_1b_3)\mathbf{j} + (a_1b_2 - a_2b_1)\mathbf{k}$$

- Magnitude

$$c = |\mathbf{a} \times \mathbf{b}| = ab \sin \theta$$

Properties of Cross-product

$$\mathbf{a} \times (\mathbf{b} \times \mathbf{c}) = (\mathbf{a}^T \mathbf{c})\mathbf{b} - (\mathbf{a}^T \mathbf{b})\mathbf{c}$$

$$\mathbf{a}^T (\mathbf{b} \times \mathbf{c}) = \begin{vmatrix} \mathbf{a} & \mathbf{b} & \mathbf{c} \end{vmatrix}$$

$$(\mathbf{a} \times \mathbf{1})\mathbf{b} = \mathbf{a} \times \mathbf{b}$$

$$(\mathbf{a} \times \mathbf{1}) \equiv \mathbf{A} = \begin{bmatrix} 0 & -a_3 & a_2 \\ a_3 & 0 & -a_1 \\ -a_2 & a_1 & 0 \end{bmatrix}$$

- **A** is called cross-product matrix

Differentiation of a Vector

$$\frac{d\mathbf{a}}{dt} \equiv \dot{\mathbf{a}} \equiv [\dot{a}_1 \quad \cdots \quad \dot{a}_n]^T$$

- Chain rules of differentiation

$$\frac{d}{dt} (\mathbf{a}^T \mathbf{b}) = \dot{\mathbf{a}}^T \mathbf{b} + \mathbf{a}^T \dot{\mathbf{b}}$$

$$\frac{d}{dt} (\mathbf{a} \times \mathbf{b}) = \dot{\mathbf{a}} \times \mathbf{b} + \mathbf{a} \times \dot{\mathbf{b}}$$

Linear Independence

- For a set of n independent vectors

$$\sum_{i=1}^n \alpha_i \mathbf{a}_i = \mathbf{0} \quad \Rightarrow \quad \alpha_i = 0 \quad \text{for all } i$$

Matrices

- For an $m \times n$ matrix

$$\mathbf{A} \equiv [\mathbf{a}_1 \quad \cdots \quad \mathbf{a}_n]$$

$$\mathbf{A} \equiv \begin{bmatrix} \mathbf{a}_1^T \\ \vdots \\ \mathbf{a}_m^T \end{bmatrix}$$

Determinant

- For an $n \times n$ (square) matrix

$$\det(\mathbf{A}) = |\mathbf{A}| = \begin{vmatrix} a_{11} & a_{12} & \cdots & a_{1n} \\ a_{21} & a_{22} & \cdots & a_{2n} \\ \vdots & \vdots & \ddots & \vdots \\ a_{n1} & a_{n2} & \cdots & a_{nn} \end{vmatrix} = \sum (-1)^{i+j} a_{ij} \det(\mathbf{A}_{ij})$$

- Example of a 3×3 (square) matrix

$$\begin{aligned} \det(\mathbf{A}) &= \begin{vmatrix} a_{11} & a_{12} & a_{13} \\ a_{21} & a_{22} & a_{23} \\ a_{31} & a_{32} & a_{33} \end{vmatrix} = a_{11} \begin{vmatrix} a_{22} & a_{23} \\ a_{32} & a_{33} \end{vmatrix} - a_{12} \begin{vmatrix} a_{21} & a_{23} \\ a_{31} & a_{33} \end{vmatrix} + a_{13} \begin{vmatrix} a_{21} & a_{22} \\ a_{31} & a_{32} \end{vmatrix} \\ &= a_{11}(a_{22}a_{33} - a_{23}a_{32}) - a_{12}(a_{21}a_{33} - a_{23}a_{31}) + a_{13}(a_{21}a_{32} - a_{22}a_{31}) \end{aligned}$$



Inverse

$$\mathbf{A}^{-1} = \frac{1}{\det(\mathbf{A})} \text{Adj}(\mathbf{A})$$


$$\text{Adj}(\mathbf{A}) = [(-1)^{i+j} \det(\mathbf{A}_{ij})]^T$$

- Generally the above is not used. Solution of linear equations are used
- Use Gaussian Elimination (GE) to solve

Manipulator

- It has a series of links connected by joints
→ Kinematic Chain (KC)
- Simple: When each and every link is coupled to at most two other links
 - Open: If it contains only two links (end ones) that are connected to only one link → Manipulator 
 - Closed: If each and every link coupled to two other links → Mechanism 

Joints or Kinematic Pairs

- Lower Pair
 - Surface contact: Hinge joint of a door
- Higher pair
 - Line or point contact: Roller or ball rolling
- Several Lower Pair Joints
 - Slides 5-12 of Chapter 5 

Degrees of Freedom (DOF)

- No. of independent (or minimum) coordinates required to fully describe its pose or configuration
 - A rigid body in 3D space has 6 DOF
- Grubler formula (1917) for planar mechanisms
- Kutzbach formula (1929) for spatial mechanisms

Grubler-Kutzbach Criterion

$$n = s (r - 1) - c, \quad c \equiv \sum_{i=1}^p c_i \quad \dots (5.1)$$

s : dim. of working space

(Planar, $s = 3$; Spatial, $s = 6$);

r : no. of rigid bodies or links in the system;

p : no. of kinematic pairs or joints in the system;

c_i : no. of constraints imposed by each joint;

c : total no. of constraints imposed by p joints;

n_i : relative degree of freedom of each joint;

n : DOF of the whole system.

Basically, no. of parameters used to define free links –
no. of constraints (independent) by joints

Four-bar Mechanism,

$$n = 3 (4 - 4 - 1) + (1 + 1 + 1 + 1) = 1 \quad \dots (5.4)$$

Six-DOF Manipulator

$$n = 6 (7 - 6 - 1) + 6 \times 1 = 6 \quad \dots (5.5)$$

Five-bar Mechanism

$$n = 3 (5 - 5 - 1) + 5 \times 1 = 2 \quad \dots (5.6)$$

Double Parallelogram

$$n = 3 (5 - 6 - 1) + 6 \times 1 = 0 \quad \dots (5.7)$$

Summary

- More applications in Space, Medicines, etc. were shown
- Vectors and matrices were defined
- Definitions of mechanisms, DOF, etc, were explained.

Thank You

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