Web Based Virtual Robot Prototyping and Manufacturing

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Abstract - Developing an environment that enables optimal and flexible design of robot manipulators using reconfigurable links, joints, actuators, and sensors is an essential concept towards efficient robot design and prototyping. Such an environment should have a complex set of software and hardware subsystems for designing the physical parts and the controllers, and for the algorithmic control of the robot modules (kinematics, inverse kinematics, dynamics, trajectory planning, analog control and digital computer control). Specifying object-based communications and catalog mechanisms between the software modules, controllers, physical parts, CAD designs, and actuator and sensor components is a necessary step in the prototyping activities.

In this project, we propose a web interface based prototyping environment for robot manipulators with the required subsystems and interfaces between the different components of this environment. The goal is to build a system of components that allows potential customers (located anywhere geographically) to input through a web interface a set of request / design parameters and specifications (such as torque, dexterity, repeatability, velocity etc), that could be analyzed, simulated and converted to specific manufacturing information that can be ultimately used by an automated manufacturing plant. The plant would be able to build consumer robots tailored to specific requirements and deliverable to customers flexibly.

I. INTRODUCTION

Designing and building an electro-mechanical system such as a robot manipulator, require a diverse series of tasks, starting with specifying the tasks and performance requirements, determining the robot configuration and parameters that are most suitable for the required tasks, ordering/manufacturing the parts and assembling the robot, developing the necessary software and hardware components (controller, simulator, monitor), and finally, testing the robot and measuring its performance.

Our goal is to build a framework for the optimal and flexible design of robot manipulators with the required software and hardware systems and modules that are independent of the design parameters, so that it can be used for different configurations and varying parameters. Figure 1 shows a schematic view of the prototyping environment with its sub-systems and the interface.

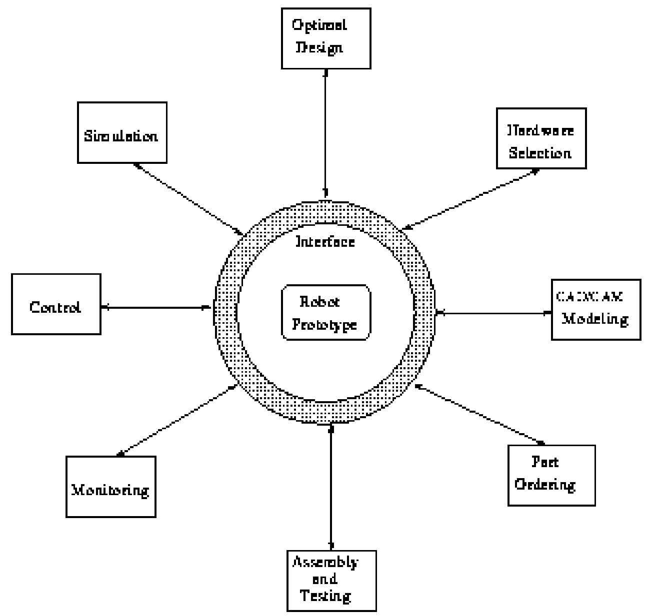

Figure 1: The prototyping environment.

The task will imply various types of integrations, ranging from the development of a web interface, the design and consideration of software simulators and controllers to the design of hardware controllers, parts and automated (robotized) manufacturing facilities. To make the proposed model truly accessible and marketable, the set of requirement tasks, torques, dexterity, repetability etc will be integrated into a web based portal, hence easily access through a URL.

II. BACKGROUND / EXISTING WORK

To integrate the work among different teams and sites working within such a large project, there must be efficient synchronization to facilitate the communication and cooperation between the different design groups. A concurrent engineering infrastructure that encompasses multiple sites and subsystems, called Palo Alto Collaborative Testbed (PACT), was proposed in [2]. The issues discussed in that work were: cooperative development of interfaces, protocols, and architecture, sharing of knowledge among heterogeneous systems, and computer-aided support for negotiation and decision-making.

An execution environment for heterogeneous systems called "InterBase" was proposed in [1]. It integrates preexisting systems over a distributed, autonomous, and heterogeneous environment via a tool-based interface. In this environment each system is associated with a Remote System Interface (RSI) that enables the transition from the local heterogeneity of each system to a uniform system-level interface.

Object orientation and its applications to integrate heterogeneous, autonomous, and distributed systems are discussed in [5]. The argument in this work is that object-oriented distributed computing is a natural step forward from the client-server systems of yesterday. Automated, flexible and intelligent manufacturing based on object-oriented design and analysis techniques is discussed in [4], and a system for design, process planning and inspection is presented.

A management system for the generation and control of documentation flow throughout a whole manufacturing process is presented in [3]. The method of quality assurance used to develop this system covers cooperative work between different departments for documentation manipulation.

A computer-based architecture program called the Distributed and Integrated Environment for Computer-Aided Engineering (DICE), which addresses the coordination and communication problems in engineering, was developed at the MIT Intelligent Engineering Systems Laboratory [6].

A prototyping envirnoment for robot manipulators and a 3-link manipulator protopype have been developed at Utah (Utah Prototying Environment [UPE] and Utah Robot Kit [URK]) [7, 8].

Various controlling, simulation and optimization methods have been succesfully presented and exercised on custom manipulators such as a tire changing manipulator, a generic 6 DOF manipulator, etc [9,10,11,12,13]

The Ternopil Academy of National Economy (TANE) team has produced extensive work on controller development including development of controller structures, controller hardware and software, reconfigurable SHP and IOS [14,15,16,17,18,19,20,21].

III. IMPLEMENTATION CONSIDERATIONS

Overall Design

The Prototyping and Manufacturing Environment (PME) consists of a central interface (CI) and subsystem interfaces (SSI). The tasks of the central interface are to:

- Maintain a global database of all the information needed for the design process.
- Communicate with the subsystems to update any changes in the system. This requires the central interface to know which subsystems need to know these changes and send messages to these subsystems informing them of the required changes.
- Receive messages and reports from the subsystems when any changes are required, or when any action has been taken (e.g., update complete).
- Transfer data between the subsystems upon request.
- Check constraints and apply some of the update rules.
- Maintain a design history containing the changes and actions that have been taken during each design process with date and time stamps.
- Deliver reports to the customer with the current status and any changes in the system.

Consumer Preset Constraints, Task Specifications and Requirements

All constraints are saved in a database (likewise the update rules). This makes the data entry scalable. A customer can add, update, and delete any constraint or update rule through a web portal.

Complicated data structures are not required for evaluation. The database is very simple, which facilitates maintaining the design history.

By analyzing the design constraints and the update rules, an adequate dataset will be passed through the CI to the Controller Simulator Block (CSB).

Controller / Controller Simulator Block Design

The first step in the design of the controller for a manipulator is to solve for its kinematics, inverse kinematics, dynamics, and the feedback control equation that will be used; the type of input and the user interface should be determined at this stage too.

For trajectory generation, cubic polynomials method will be considered, which generates a cubic function that describes the motion from a starting point to a goal point in a certain time. The error in position and velocity is calculated using the readings from the sensors. The control module simulates a PD controller to minimize that error. The error depends on several factors such as: frequency of update, frequency of sensors reading, and the desired trajectory (for example, if we want to move a large number of degrees in a very small time interval, the error will be large).

The CSB will function in direct feedback through the CI with the customer web portal, such as to allow changes to the constraint sets until they qualify as valid for the manufacturing possibilities.

Once the adequate dataset has been analyzed and solved through the CSB, the CI will pass the relevant information to the robotized manufacturing facility (RMF).

The Robotized Manufacturing Facility

In order to completely isolate the robot manufacturing from comprehensive human operator interventions, a robotized manufacturing facility / plant is considered. The plant will be composed of robot manipulators itself, and will be responsible for assembling the parts based on the provided information from a successful CSB execution. An extensive collection of "universal" hardware parts will be available for this purpose, so that satisfactory varieties of robots can be constructed with same parts.

IV. DESIGN APPROACH

To assure consistent viability, in the early stages of the proposed project, the focus will fall on fairly simplified sets of input parameters and "output" manipulators. Specifically the designable robots will resume to limited torque, mobility and visual interface requirements, then hopefully reaching the levels of automation / performance desired in industrial scale manipulators, based on the financial and intellectual resources and interests available .

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