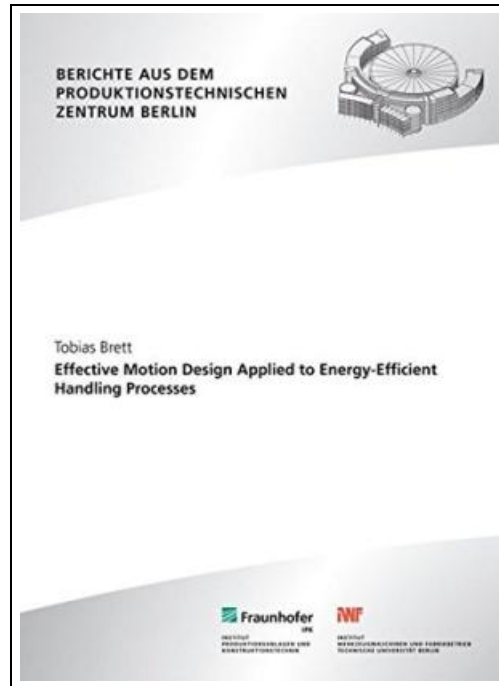


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(Annette Boyle)

EFFECTIVE MOTION DESIGN APPLIED TO ENERGY-EFFICIENT HANDLING PROCESSES



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Fraunhofer IRB Verlag. Paperback. Condition: new. BRAND NEW, Effective Motion Design Applied to Energy-Efficient Handling Processes, Tobias Brett, Berlin Fraunhofer IPK, Gunther Seliger, Industrial robots are available in a large variety of mechanical alternatives regarding size, motor power, link length ratio or payload. The four major types of serial kinematics dominating the market are complemented by various parallel kinematics for special purpose. In contrast, few other path planning alternatives are applied in industrial robotics which are based on similar analytic solution principles. The objective of this thesis is to develop a systematic design method for artifacts in motion, to integrate motion design and mechanical design to enable new processes for production. For each design, a theoretical benchmark is developed, which cannot be attained by conventional robots in principle. A key performance indicator enables to measure the degree of goal achievement towards the benchmark during all design phases. Motion behaviors are identified on a local level by dynamic systems modeling and are integrated into new global behavior featuring a new quality, suitable for exceeding the design benchmark in industrial processes. Two exemplary handling robot designs are presented. The first concept enables motion behavior to consume less electrical power than kinetic energy transferred to and from its payload during motion. The second concept enables motion with four degrees of freedom by single motor stimulation, reducing idle power consumption on factor 4 towards conventional robots.



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