DESIGN OF AN AUTOMATED PUNCHING SYSTEM FOR REFRIGERATOR DOOR MANUFACTURING PROCESS

Master of Science dissertation



Department of Electrical Engineering University of Moratuwa, Sri Lanka

March 2011

iniversity of Moratuwa





LIBRARY
UNIVERSITY OF MORATUWA, SRI LADE.
MORATUWA

18/20/80/2011

DESIGN OF AN AUTOMATED PUNCHING SYSTEM FOR REFRIGERATOR DOOR MANUFACTURING PROCESS

A dissertation submitted to the Department of Electrical Engineering, University of Moratuwa in partial fulfillment of the requirements for the degree of Master of Science

by



Supervised by Dr. Udayanga Hemapala

Department of Electrical Engineering University of Moratuwa, Sri Lanka

March 2011

9680M

621.3 "11"
621.3 (04.3)

BUSHARY S

DECLARATION

The work submitted in this dissertation is the result of my own investigation, except where otherwise stated.

It has not already been accepted for any degree, and is also not being concurrently submitted for any other degree.

UOM Verified Signature

G.T\Galagedarage

15-02-2011

University of Moratuwa, Sri Lanka. Electronic Theses & Dissertations www.lib.mrt.ac.lk

We/I endorse the declaration by the candidate.

⁶ UOM Verified Signature

Dr. Udayanga Hemapala.

CONTENTS

A A Li	st of	ct		i iv v viii
1	In	troduc	ction	1
	1.1	Bac	kground	1
	1.2	Mot	tivation	4
	1.3	Goa	lls and Scope of present work	7
2	St	ateme	ent of the problem	11
	2.1	Prel	liminaries	11
	2.2	Prol	blem Identification	13
	2.2	2.1	Punching Input bay	13
		2.2.1.3	1 Sheet skewing	13
		2.2.1.2	2 Frictional losses	14
		2.2.1.3	Sheet presence & positioning & Dissertations	15
		2.2	Gripper Mechanismb.mrt.ac.lk	
3	Th	eoreti	ical Development	18
	3.1	Syst	em Analysis	18
	3.1	1.1	Punching input Bay.	18
	:	3.1.1.1	Remove sheet skewing	18
		3.1.1.2	2 Reducing frictional losses	21
		3.1.1.3	Identification of Sheet presence & positioning	26
	3.1	1.2	Gripper Mechanism.	29
	:	3.1.2.1	Gripper Tool & Mechanical construction	30
	;	3.1.2.2	2 Wheels & Track of Gripper mechanism	35
4	Ma	athem	atical Analysis	38
	4.1	Kine	matic Analysis of Gripper Mechanism	38
	4.2	Dyna	amic Analysis of Gripper mechanism	43
	4.2	2.1	Motion along Y axis	43
	4.2	2.2	Motion along X axis	45

4	4.2.3	Gripper Rotational Motion about the axis passing point 'A'.	. 46
4.3	l Plar	nt Design	. 48
4	4.3.1 [.]	Plant for translation along Y axis	. 48
4	4.3.2	Plant for translation along X axis.	. 52
4	4.3.3	Controller for rotation about axis passing point A.	. 56
5 F	PID Con	troller Design & Analysis	.59
5.1	. Tim	e domain Analysis of Proportional Controller System	. 59
9	5.1.1	Translation along Y axis	. 59
9	5.1.2	Translation along X axis.	. 61
5	5.1.3	Rotation about a axis passing point A	. 62
5.2	PID	Controller Design	. 63
į	5.2.1	Translation along Y axis.	. 63
5	5.2.2	Translation along X axis.	. 70
9	5.2.3	Rotation about a axis passing point A	. 73
5.3	S Sim	ulation of analytical results:	. 76
5	5.3.1	Simulation University of Moratuwa, Sri Lanka.	
5	5.3.2	Simulation of X axis motion Simulation of X axis motion Wyyyy lib mrt ac lk	. 80
5	5.3.3	www.lib.mrt.ac.lk Simulation for rotation about a axis passing point A	. 81
6 (Control	Logic Development	. 84
6.1	. Defi	initions & Parameters	. 84
6.2	. Logi	ic Algorithm.	. 85
6.3	Tran	nsducer Logic design	. 87
7	Concl	usion	89
Refe	rences		90
Appe	endix A	Data sheet for Inductive proximity sensor.	91
Appe	ndix B	Data sheet for Magnetic Gripper.	92
Appendix C		Data sheet for DC Servo Motor.	93

Abstract

Regnis Lanka (PLC) is a leading manufacturer in Refrigerators, has identified a bottle neck in its manufacturing process of Refrigerator doors. There is a semi automated Hydraulic punching machine which consumes one operator for metal sheet feed in, positioning and feed out after been punched. This consumes about 40 seconds to complete a single punched sheet and it has reduced the total capacity of the whole manufacturing line to 500 Refrigerators per a shift. Factory is in the position of automating the door manufacturing system nearly to double the capacity by reducing the punching cycle time.

As a part of the project to fulfill the requirements of an automated punching system, A 3-DOF magnetic gripper mechanism for metal sheet feed in, positioning & feed out of the sheet from punching machine along with a sheet input bay to support all the 3 degree of movements of the sheet is designed. A controller with Control logic is designed for all mechanical movements. The verification of controller was done by MATLAB for analysis and physical model been created by SOLID WORKS.





Acknowledgement

Thanks are due first to my supervisor, Dr. Udayanga Hemapala, and co supervisor Dr. Harsha Abeykoon for their great insights, perspectives, guidance and sense of humor. My sincere thanks go to the officers in Post Graduate Office, Faculty of Engineering, University of Moratuwa, Sri Lanka for helping in various ways to clarify the things related to my academic works in time with excellent co-operation and guidance. Sincere gratitude is also extended to the people who serve in the Department of Electrical Engineering office.

Lastly, I should thank many individuals, friends and colleagues who have not been mentioned here personally in making this educational process a success. May be I could not have made it without your supports.



List of Figures

Figure	Page
Figure 1.1: (a) Front view of existing punching machine. (b) Side view	1
Figure 1.2: Top view of Punching Bed	2
Figure 1.3: Sheet Flow and Available Stacks	3
Figure 1.4: Flow diagram of manual punching process	5
Figure 1.5: Final drawing of completed System	8
Figure 2.1: Top view of punching sheet bay	11
Figure 2.2: Side view of punching sheet bay	12
Figure 2.3: Sheet skewing at vertical movement	14
Figure 2.4: Sensor Locations	16
Figure 2.5: Gripper face & limitations for Gripper movement	17
Figure 3.1: Punching bay	18
Figure 3.2: Analysis of sheet skewing	19
Figure 3.3: Vertical sheet movement on roller	22
Figure 3.4: Friction on Left & Right roller segments	24
Figure 3.5: Friction of Sheet Left-Right motion	25
Figure 3.6: Final input bay top view	26
Figure 3.7: Wedge for bearing mounting.	26
Figure 3.8: Inductive Proximity Sensor of Moraturwa; Sri Lanka:	27
Figure 3.9: Sensor mounting method & dimensions.	27
Figure 3.10: Sensor Locations on input punching bay	28
Figure 3.11: Gripper mechanism.	29
Figure 3.12: Gripper mechanism movements	30
Figure 3.13: Forces acting on Magnetic Gripper	
Figure 3.14: Magnetic gripper	32
Figure 3.15: Magnetic Gripper mechanism	32
Figure 3.16: (a) Front view of gripper mechanism alone. (b) Front view of gripper	
mechanism fixed on to input bay	
Figure 3.17: DC Servo motor	
Figure 3.18: Block diagram of Servo Amplifier (By courtesy of McLennan)	
Figure 3.19: Wheel Track & wheels of gripper mechanism	
Figure 3.20: Complete gripper mechanism design	
Figure 3.21: Back view of Gripper mechanism.	37
Figure 4.1: (a) Home Position of Gripper Tool with out sheet. (b) Home position of	
Gripper Tool with Sheet	
Figure 4.2: Work space of Gripper tool.	
Figure 4.3: Positions of Gripper hand frame.	
Figure 4.4 : Sheet positions on punching bay. (a) Sheet is just released $\&$ the tool is in	
HP	
Figure 4.5: Gripper Motion along Y axis	. 44

Figure 4.6: Gripper motion along X axis	45
Figure 4.7: Gripper rotation about point A	46
Figure 4.8: Complete Control Block diagram for Y direction motion	50
Figure 4.9: Simplified Control Block Diagram in Y direction movement	51
Figure 4.10: Complete Control Block diagram for X direction motion	53
Figure 4.11: Simplified Control Block Diagram in X direction movement	54
Figure 4.12: Complete Control Block diagram for rotation about an axis passing point A	57
Figure 4.13: Control block diagram of rotation about axis passing point A	58
Figure 5.1: Time Domain Response for unity proportional controller for Y axis motion	60
Figure 5.2 :Time Domain Response for unity proportional gain controller for X axis	
motion	61
Figure 5.3: Time Domain Response for unity proportional controller Gain for rotational	1
motion	63
Figure 5.4: Time Domain Analysis of Motion along Y axis at Critical damp	65
Figure 5.5: Time Domain Analysis for motion along Y axis with PD Control	67
Figure 5.6: Pole Zero map of closed loop transfer function for motion along Y axis	67
Figure 5.7: PID Control Block for Y direction motion	69
Figure 5.8: Time Domain Analysis of PID Controlled System in Y direction	70
Figure 5.9: Time Domain Analysis of the System motion along X axis	72
Figure 5.10: PID Controlled Control Block Diagram for motion along X axis	
Figure 5.11: Time domain analysis of system rotation about a axis passing point A	74
Figure 5.12: Time Domain Analysis of PID controlled system for Rotation WWW.ib. nit. ac. lk Figure 5.13: Complete Control Block Diagram for PID controlled System for Rotation	75
Figure 5.13: Complete Control Block Diagram for PID controlled System for Rotation	76
Figure 5.14: Simulation Block Diagram for Y axis motion	76
Figure 5.15: Simulation result at Servo Amplifier Input	
Figure 5.16: Simulation result at servo amplifier out put	
Figure 5.17: Simulation out put after servo gain reduced to 2	78
Figure 5.18: Simulation out put after PID tuning & servo gain reduced to 2	78
Figure 5.19: Simulation results at servo amp out put after PID tuning and servo gain	
reduced to 2	
Figure 5.20: Final PID tuned simulation block diagram for Y axis motion	79
Figure 5.21: Final PID tuned Simulation Block Diagram for X axis motion	80
Figure 5.22: Simulation out put after PID tuning & servo gain reduced to 2, in X motion	.80
Figure 5.23:Simulation results at servo amp out put after PID tuning and servo gain	
reduced to 2, in X motion	
Figure 5.24: Simulation Block Diagram for rotation about axis A	81
Figure 5.25: Simulation out put before PID tuning in rotational motion	82
Figure 5.26: Final PID Tuned Simulation Block diagram of rotational motion	
Figure 5.27: Final out put of PID tuned system of rotational motion	
Figure 5.28: Simulation at servo amp out put after PID tuning in rotational motion	
Figure 6.1: Gripper positions & Magnets	84

List of Tables

Table	Page
Table 1-1: Sheet Parameters	3
Table 1-2: Timing Chart of Existing Process	6
Table 1-3: Time line Analysis of combined processes	9
Table 1-4: Maximum time allocation for automated system	10
Table 2-1: Measurements of punching Input bay	12
Table 2-2: Static Coefficient of friction of available materials	14
Table 3-1: Servo Amplifier for motor control	35
Table 4-1: Look up table for gripper movements	41
Table 5-1: Time domain analysis with varying K _{D1}	66
Table 5-2: Rouths Table	68
Table 5-3: Time domain analysis for varying K _{P1}	69
Table 5-4: Summary of individual controller performance	70
Table 5-5: Summary of PID controller performance	73
Table 5-6: Summary of controller performance	76
Table 6-1: Maximum & Minimum Angle for each motion	87
University of Moratuwa, Sri Lanka. Electronic Theses & Dissertations www.lib.mrt.ac.lk	