

Vacuum-lift

Old solution

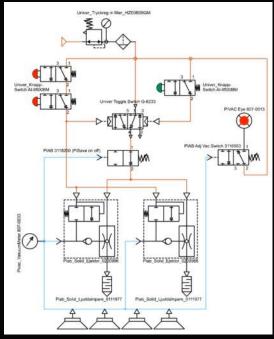
No underpressure warning No operator safety measures Exposed circuitry



New solution

Stainless steel sheetmetal interface IP-classed electromechanics & casing Auto vacuum-regulation Visual pressure feedback

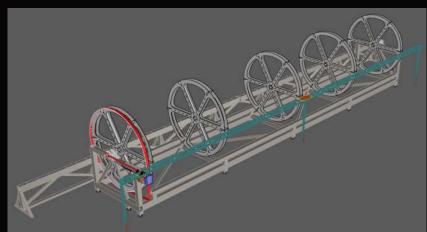






InkJet Printer

Novel composit solution (mixed build principles)
Printer drum with extreme straightness and roundness tolerances



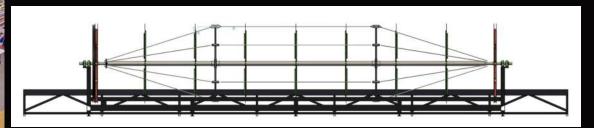




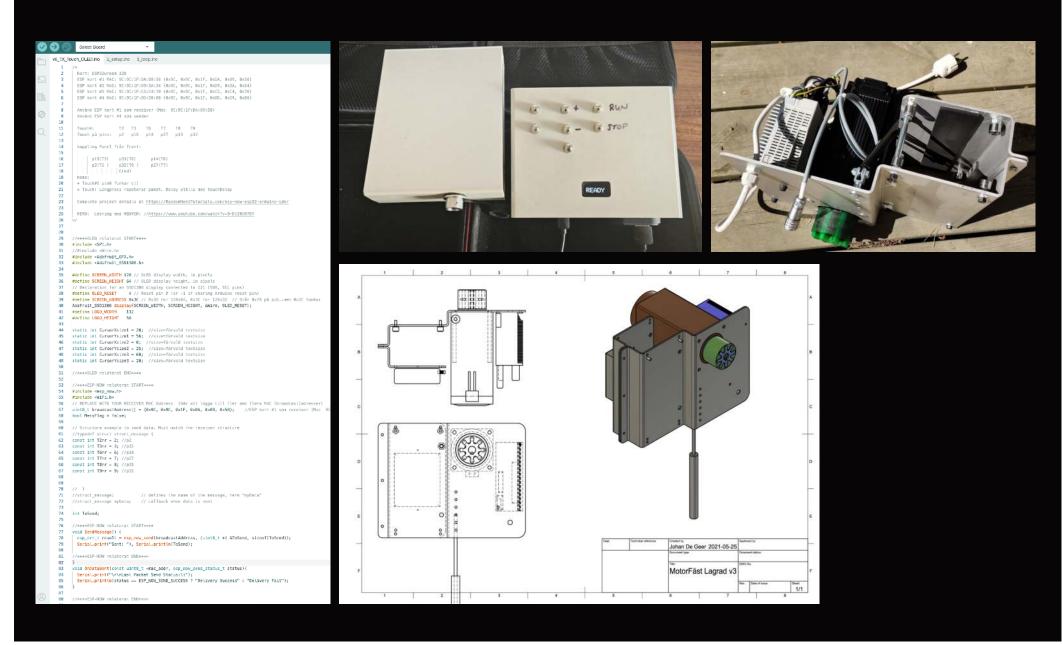




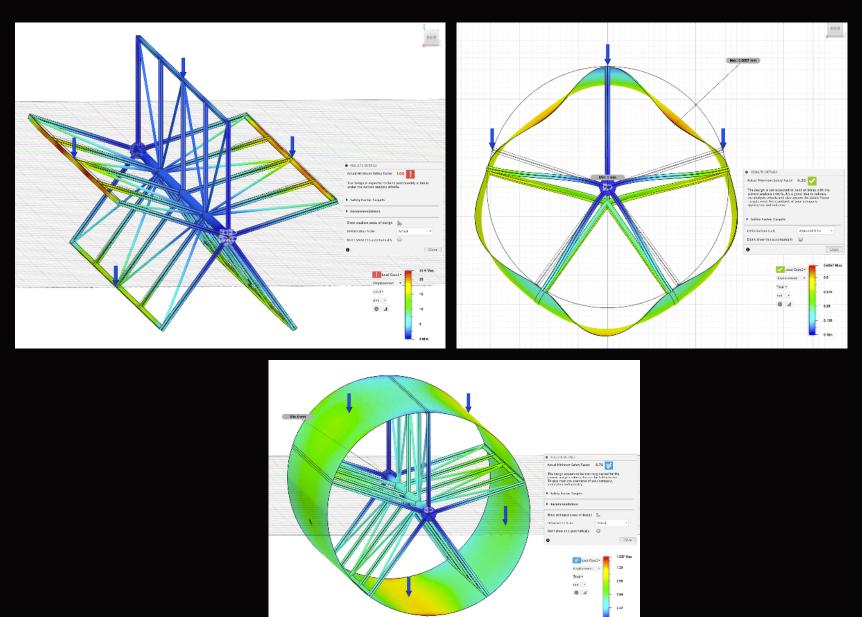




InkJet Printer: Remote Stepmotor ctrl



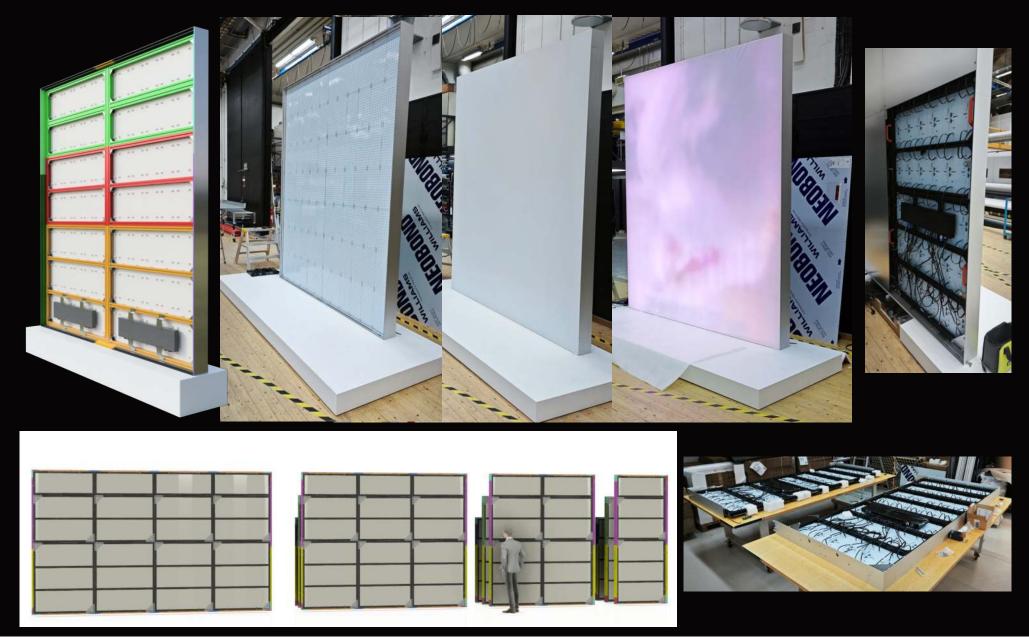
InkJet Printer: Stress simulation



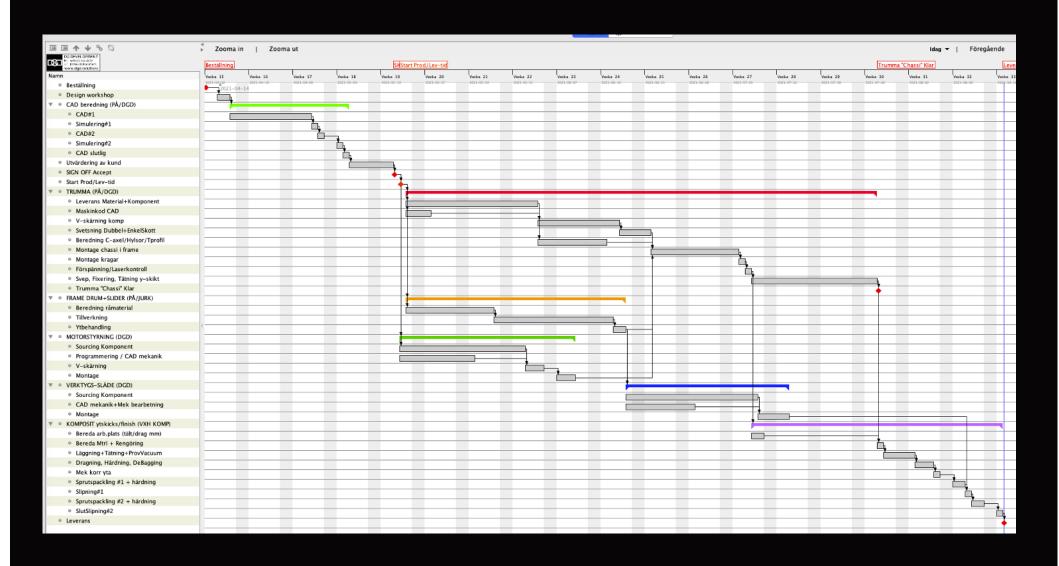
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Modular LED wall

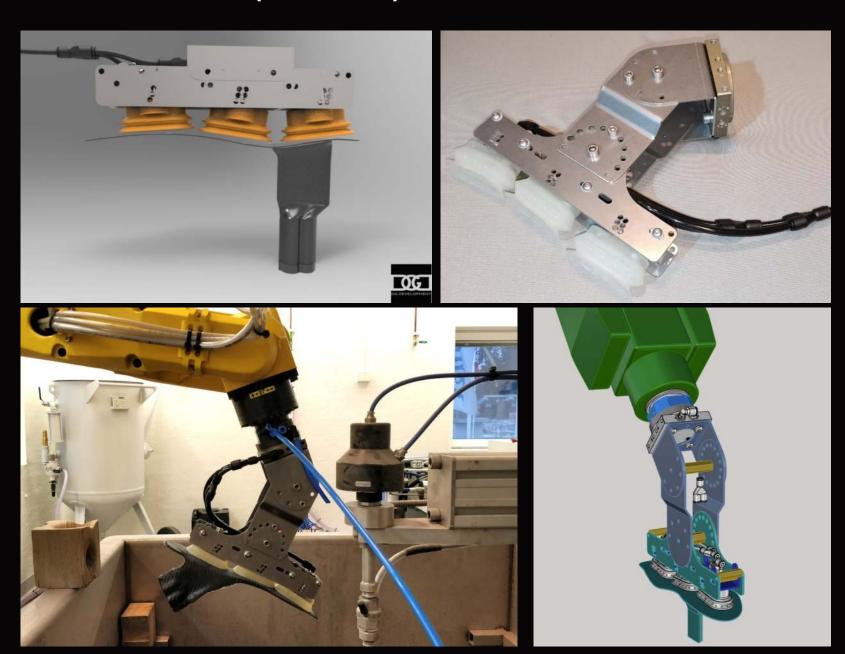
(Digital Signage)



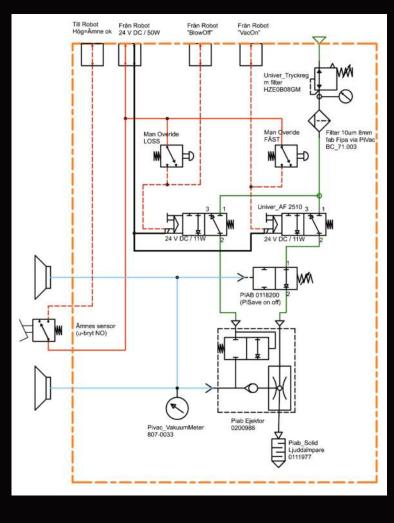
Project management



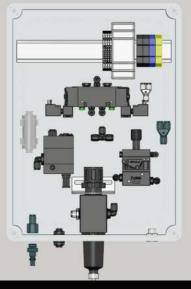
End of arm tool (EOAT)

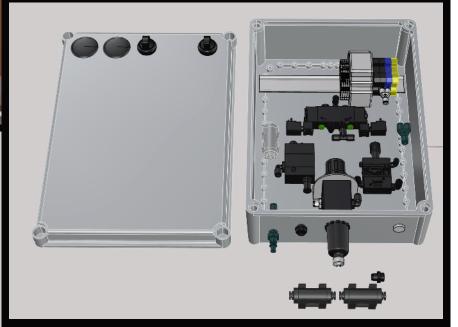


Vacuum Controller for EOAT









Barcode reader



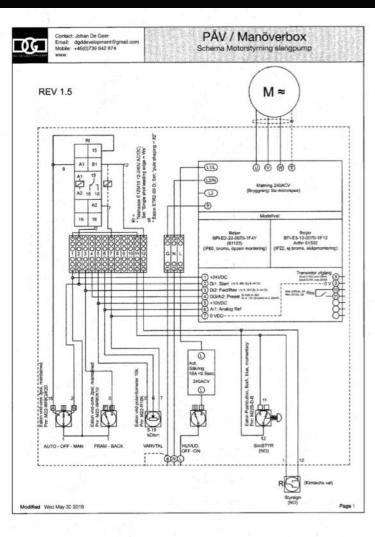




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DG DEVELOPMENT / 2020-10-12 / Johan De Geer / johan@dgd.solutions / www.dgd.solutions
const int SWrev = 7; // Program Rev
OBS OBS: Tunna linjer på la sida, Breda på 2a (bakre) sida!
Revideringsr:
v5: PulsTimeoutDefault = 5000;
v7: = v6.0 (endast förberedd copy)
v6: debug logikfel on/off switch
v6: version (SWrev)
v5: int NetSolAdjustments = 0;
                                             Nollställer kalibreringar vid läge "centrerad". Inkluderar ä
                                             Kompensering vid "linjer utan överlappning bägge riktningar"
                                       // Antal autosolenoid-tryck per justering (Läge Tidig/Sen)
const int SolRepetitionsExtrem = 10:
                                       // Antal autosolenoid-tryck per justering (Läge FörTidig / FörSen)
const int SolenoidDuty = 300;
                                       // Solenpidernas På/Av tid i mSek (= 50% duty) -- norm 300 ok
const int SkipOtyMarks = 1:
                                       // Antal märken att skippa efter senaste justerings-sekvens
const double PulsTimeoutDefault = 6000; // Tid innan reset av variabler, Längre tid ger säkrare läsning om s
bool Solenoid inwork = false:
bool SWrun_statusFlag = LOW, SWrun_newState = LOW, SWrun_oldState = LOW;
const uint8_t PuSttMtx[4]={800,801,810,811};
bool SWplus_State = LOW, SWminus_State = LOW;
int SWx = 0;
                           //Dummy för "run/reset ToggleSwitch"
bool OUstate = HIGH;
                            //OptoUpper State
bool OLstate = HIGH;
int FBTT = 0;
                            //FullByteToTest
    FlankCt = 0;
int OPcnt = 0;
                            //OnePulseCount
int Latest2bit = 0;
int NetSolAdjustments = 0; //Antal ackumulerade justeringar av solenoider
bool BUBY_Flag = false;
bool BYCH_Flag = false;
                           //BYTECHECK_Flag
long DiagnosTimer*millis();
long PulsTimeout = 8:
const byte LEDrun PinD7 = 7:
const byte SWrun_PinA8 = A8;
const byte SWplus PinA1 = Ali
const byte SWminus PinA2 = A2:
const byte ISR Upper D2 = 2:
const byte ISR Lower D3 = 3:
const byte RELAY_LEDplus_D4 = 8;
const byte RELAY_LEDminus_D5 = 9;
const byte LEDrun_D7 = A5;
 pinMode (SWrun_PinA@, INPUT);
  pinMode (SWplus_PinA1, INPUT)
  pinMode (RELAY_LEDplus_D4, GUTPUT);
   pinMode (RELAY_LEDminus_D5, OUTPUT);
   pinMode (LEDrun_D7, OUTPUT);
   attachInterrupt(digitalPinToInterrupt(ISR_Upper_D2), OPTOUPPER_EXEC, CHANGE);
  attachInterrupt(digitalPinToInterrupt(ISR_Lower_D3), OPTOLOWER_EXEC, CHANGE);
  Serial.begin(115200);
  delay(1000);
   Serial.print("**SW revision "); Serial.println(SWrev);
  Serial.println ("OBS: Tunna 4nm-linjer på la sida/tryck, Breda 10mm på 2a sidan !");
  Serial.print ("Antal marken att skippa efter senaste justering: "); Serial.println(SkipQtyMarks);
  Serial.print ("Punkter (.) indikerar auto-reset av pulsräknare (PulsTimeoutDefault): ");
  Serial.print(PulsTimeoutDefault/1000);
  Serial.println (" Sek efter att ingen puls detekterats");
```

3 phase motor control







Factory automation: Process control of HeavyDuty

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