EVAN LIN MECHANICAL ENGINEERING AT PURDUE UNIVERSITY



CYCLIC THRUST MODULATED HELICOPTER



What?

 Designed and built a model helicopter with hinged blades and specialized control loops instead of a traditional swashplate mechanism

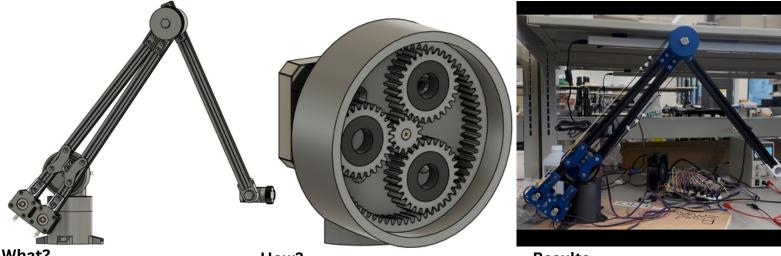
How?

- Modeled using SolidWorks
- Simulated PID loops using MATLAB Simulink
- Wired a custom flight controller with inertial measurement unit, rotary encoder, RC receiver, and motors

Results

• Full control over yaw, pitch, and roll while requiring 75% less moving parts compared to swashplate rotors

ROBOTIC ARM WITH 5 DEGREES OF FREEDOM



What?

- Designed a 5 degree of freedom robotic arm based on Arduino and **NEMA 17 stepper motors**
- Optimized for ease of assembly and reproducibility with 3D printed parts to encourage STEM education within high schools

How?

- Modeled all components using **Fusion** A final prototype has been 360
- Incorporated interference and screw joints for simplicity
- Used geometry tools to generate gear tooth profiles suitable for 3D printing

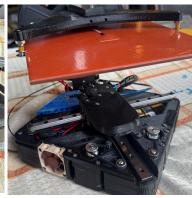
Results

- assembled and plans have been made available for high schools
- RC controlled for accessibility
- Interchangeable end effectors
- Belt-driven to reduce moving weight

INVERTED COREXY 3D PRINTER







What?

- Designed a 3D printer with an upside-down Core-XY motion at the base
- high build volume to footprint ratio
- toolend and bed holder

How?

- Used **SolidWorks** to fit all components around a 3D printed chassis
- system to concentrate moving mass Integrated fan ducts and wire channels for proper heat dissipation
- Prioritized **space efficiency** with a Implemented **DFA principles** to reduce parts required and assembly cost
- Developed a robust and lightweight Build using 3D printing and machining

Results

- 400% higher build area to footprint ratio compared to traditional printers (Prusa Mk4)
- Achieves print speeds of 220 mm/s, reducing print time by 30% on average
- Removable bed allows for quick turnaround time