

Design of a Portable Control Platform for Rod-Driven Continuum Parallel Robots

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To my mother, Gildes Ester.

Success is the sum of small efforts, repeated day in, and day out.

— Robert Collier

Abstract

This project focuses on designing and implementing a portable, modular, and scalable platform alongside a control system tailored for rod-driven continuum parallel robots. The main goal was to develop a versatile mounting solution facilitating efficient robot movement across diverse applications. The project involved the design and construction of the mounting platform, as well as the development of the control interface. A rod-driven continuum parallel robot was designed and implemented, with a focus on miniaturization and optimization of the structure. Additionally, the project aimed to implement a customized language specification for programming the linear actuators, enabling tailored control and operational flexibility. Furthermore, an application was developed to interface with the control system, utilizing the created protocol to ensure seamless communication and precise control.

Acknowledgements

I want to thanks to God...

Contents

List of Figures	viii
List of Tables	x
1 Introduction	1
1.1 Objectives	4
1.1.1 General Objective	4
1.1.2 Specific Objectives	4
2 Target Robot Structure	6
2.1 Reference Model	6
2.2 Rod Material	7
2.3 Design and Dimensions	9
2.4 Ring Constraints	11
3 Linear Actuator	13
3.1 Motor	16
3.2 First model	18
3.3 Final model	19
3.4 Specifications	22
4 Platform Assembly	24

4.1	Electronics Case	24
4.1.1	Circuit Schematic	24
5	Control System Interface	28
5.1	Protocol Specifications	28
5.2	Command Line Application	32
5.2.1	Architecture	32
5.2.2	Usage	32
5.3	PID Control and Tuning	32
5.3.1	Test Data	32
5.3.2	System Identification	32
5.3.3	PID Tuning	32
6	Performance and Results	37
Conclusions		41
Future Work and Recommendations		42
Bibliography		43
Appendices		45
A	Forces in Actuator Arm	46
B	PID Tuning Code	46
C	Test Code	47
D	Command Line Interface Source Code	47
E	Firmware Source Code	49
E.1	Arduino Main Entry Point	49
E.2	Persistence Memory Management Class Header	50
E.3	Persistence Memory Management Class	50
E.4	Commands Definitions	51

E.5	Actuators Instances	55
E.6	Actuator Class Header	57
E.7	Actuator Class	58

List of Figures

1.1	Traditional parallel robots	2
1.2	Continuum robots with extrinsic actuation	3
2.1	Reference robot structure	7
2.2	Constraints and range of motion	7
2.3	Maximum deflection and point load	9
2.4	Robot body constraints and parts	10
2.5	Robot body lateral views	10
2.6	Ring constraint	11
2.7	Ring constraint sizes	12
2.8	Closed-form pair constraint	12
3.1	Linear motion systems	13
3.2	3D printer extruder	14
3.3	Extruder without heater	15
3.4	Actuators arrange	15
3.5	Gear motor N20 with encoder	17
3.6	Dimensions of gear motor N20 with encoder	17
3.7	First model isometric view	18
3.8	First model dimensions	19
3.9	Final model isometric view	19

3.10	Final model dimensions	20
3.11	Actuator assembly exploded-view	21
3.12	Forces in actuator arm	22
3.13	Friction force in rod	23
4.1	Platform assembly exploded-view	25
4.2	Electronics assembly exploded-view	25
4.3	Ports and connections	26
4.4	Main circuit schematic	27
4.5	Motor circuit schematic	27
5.1	Relationships of control system components	29
5.2	System flowchart	29
5.3	Command line usage	30
5.4	Command line connection	31
5.5	Command line manual input	31
5.6	Command line file parsing	34
5.7	Input and output signals	34
5.8	Transfer function identification in MATLAB	35
5.9	Transfer function model in MATLAB	35
5.10	Blocks diagram of control system	35
5.11	System response of simulation in Simulink	36
6.1	Arm segments	38
6.2	One segment arm positions	38
6.3	Electronics case and connections	39
6.4	Complete prototype	39
6.5	Linear actuator issues	40

List of Tables

2.1	Fiberglass and AISI 302 steel properties	8
2.2	Comparison between Wu & Shi (2022) model and custom test model	8
3.1	Gear motor specifications	17
3.2	Actuator assembly parts list	21
3.3	Actuator specification	23
4.1	Platform assembly parts list	24
4.2	Electronics assembly parts list	26
5.1	G-Code definitions	28
5.2	M-Code definitions	30
5.3	G-Codes usage	32
5.4	M-Codes usage	33
5.5	Code parameters	33
5.6	PID Tunings	33
6.1	Platform specifications	37

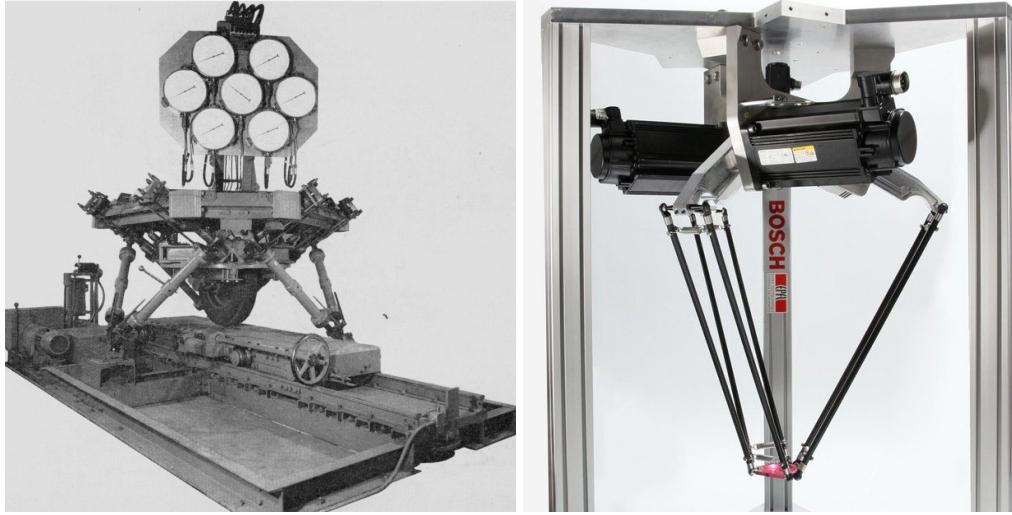
Chapter 1

Introduction

Robots in general can be categorized into serial and parallel types. Serial robots are characterized by a series of linked joints while parallel robots have multiple axes that move in parallel, usually working together to support a single platform.

Parallel robots represent a significant branch in the field of robotics due to their precision and versatility in various applications such as pick-and-place manipulation, simulators, manufacturing, and tooling, among others. As described in [1], these applications span both industry and medicine, leveraging the high rigidity, precision, and speed of these robots to compensate for the performance limitations of serial robots.

The origin of parallel robots dates back to the 1960s with the development of the Gough-Stewart [2] parallel mechanism (Figure 1.1a), which has become one of the most iconic in the field of parallel robotics. Later, in the 1980s, Reymond Clavel designed a robust parallel structure with three translational degrees of freedom and one rotational degree of freedom, as illustrated in Figure 1.1b. This robot, known as the Delta Robot, has become one of the most significant examples in the field of parallel robotics.



(a). Gough-Stewart Platform

Source: Adapted from [2]

(b). Clavel's Delta Robot

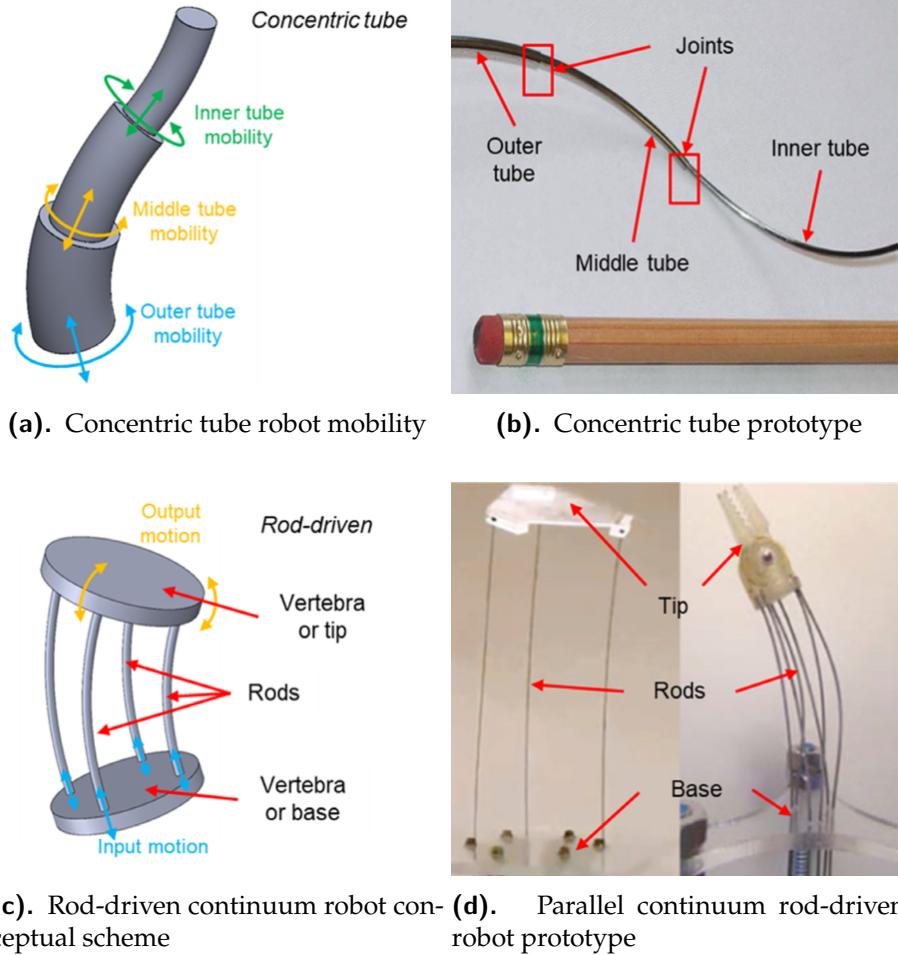
Source: Adapted from [3]

Figure 1.1: Traditional parallel robots

Another distinguishing feature of these robots is the presence of multiple closed kinematic chains that connect and move the mobile platforms, in contrast to serial robots, which operate with an open kinematic chain and move in a linear sequence. However, according to Briot and Kahrs [4] the fundamental questions about this class of robots have been addressed. As a result, in recent years, interest in parallel robots has shifted towards exploring new alternatives.

Current research in robotics transcends conventional definitions, pushing the boundaries of this field and fostering new possibilities and innovations. Briot and Kahrs [4] illustrate how parallel manipulators have been integrated into various novel robot types, such as continuum robots, flying robots, cable-driven robots, underactuated robots, multi-fingered hands, and microscale parallel robots. However, this emerging class of robots presents significant scientific challenges in design, modeling, and control. Among these categories, aerial robots, parallel robots, and continuum or soft robots are particularly noteworthy for their ability to venture into new areas due to their lightness and flexibility.

Expanding on these insights, Russo et al. [5] offer a comprehensive review

**Figure 1.2:** Continuum robots with extrinsic actuation

Source: Adapted from [5]

focusing on recent advancements, current limitations, and ongoing challenges in the design, modeling, and control of continuum robots. They classify continuum robots based on their design, distinguishing them by their extrinsic or intrinsic actuation methods. Extrinsic actuation (Figure 1.2) involves transmitting motion from the robot's base along its structure, categorized into three main families depending on the transmission elements used: tendon-driven, concentric tube (Figures 1.2a, 1.2b), and rod-driven robots (Figures 1.2c, 1.2d). Furthermore, robots with intrinsic actuation employ actuators integrated into their structure to generate movement, meaning the actuation occurs within the robot's body.

Current challenges in designing and modeling parallel continuum robots in-

clude improving performance through miniaturization of actuators, integrating with rigid robots, exploring smart materials, precise environmental modeling, and implementing proprioception with new sensors [5]. Modeling efforts also focus on representing interaction environments and improving real-time implementations, alongside standardizing simulation environments. Control challenges involve ensuring precise manipulation and adapting to dynamic environments using advanced sensor technology and adaptive strategies.

This project aims to address the efficiency challenges of continuum robots through the miniaturization of their parallel linear actuators. Specifically, it focuses on implementing adaptive control strategies for diverse applications using an extrinsic actuation platform for rod-driven continuum robots. This research endeavors to enhance affordability and user-friendliness, aiming to broaden adoption and usability in practical contexts.

1.1 Objectives

1.1.1 General Objective

Design and develop a portable, modular, and scalable platform with a control system for the actuation of rod-driven continuum parallel robots.

1.1.2 Specific Objectives

- Adapt an existing design of a rod-driven continuum parallel robot, optimizing it for reduced size while maintaining functionality and performance.
- Design linear actuators that provide precise control and enable dexterous movements, ensuring high accuracy and reliability.
- Fabricate all necessary components and assemble a fully functional physical

prototype of the platform, adhering to the design specifications.

- Implement a customized language specification for programming the linear actuators, allowing for tailored control and flexibility in operations.
- Develop an application to interface with the control system, utilizing the created protocol to facilitate seamless communication and control.
- Conduct comprehensive experimental testing and validation of the system, ensuring it meets all performance criteria and operational standards.

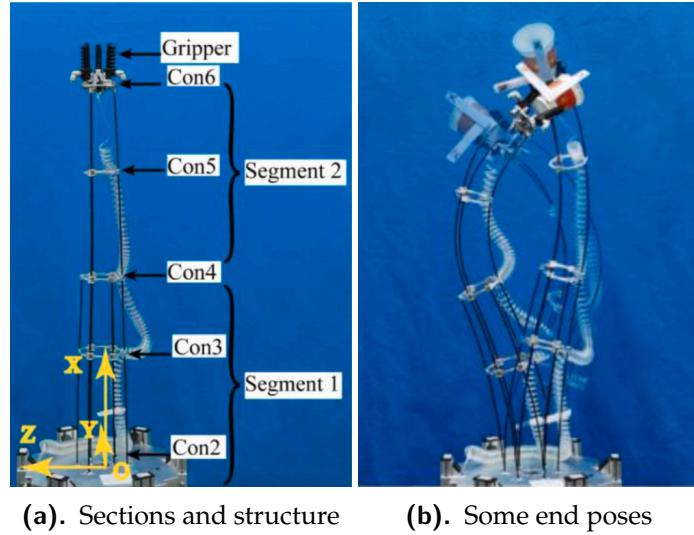
Chapter 2

Target Robot Structure

Rod-driven Continuum Parallel Robots (RDCPR) represent a relatively new class of robots characterized by their unique rod-driven actuation mechanism. Limiting and defining the dimensions and structure of these robots is crucial for the development of the platform, which aims to facilitate their movement and operation in various applications. In the following sections, a detailed exploration will be conducted on the configuration and essential components that define the structure and operational capabilities of the RDCPR.

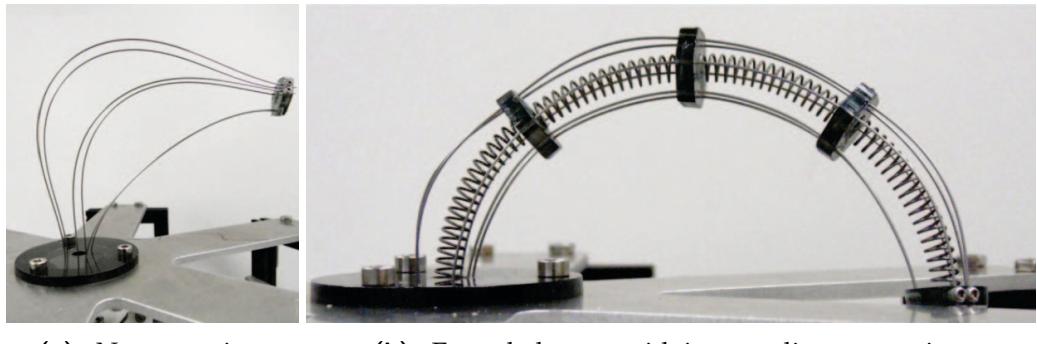
2.1 Reference Model

The reference model, depicted in Figure 2.1, was developed by Wu and Shi [6]. It was chosen due to its representation as one of the most comprehensive RDCPR designs, showcasing versatility and a wide range of motion. With 5 DoFs, it features two independently manipulable segments, making it extensible.

**Figure 2.1:** Reference robot structure

Source: Adapted from [6]

The inclusion of intermediate constraints, as illustrated in Figure 2.2, enhances the robot's operational range.

**Figure 2.2:** Constraints and range of motion

Source: Adapted from [7]

2.2 Rod Material

A rod, denoted as r , is defined with the inequality $L \gg r$, where L represents its length and r its radius. In the reference model, rods are constructed from fiber-glass, while in Figure 2.2, they are made from steel. These materials are commonly

used due to their high stiffness and ability to withstand significant bending without plastic deformation or fracture. Steel alloys like AISI 302, commonly used in springs, exemplify these properties well. Table 2.1 details the material properties of AISI 302 steel and fiberglass.

Table 2.1: Fiberglass and AISI 302 steel properties

Symbol	Property	Fiberglass	AISI 302
ρ	Density [g/cm^3]	2.6	8.0
E	Young's Modulus [GPa]	85	187.5
G	Shearing Modulus [GPa]	36	70.3

While the Cosserat rod model [5] is commonly used for analyzing these robots, understanding the maximum deflection that a rod can withstand involves applying the Euler-Bernoulli beam equation 2.1, where I is given by equation 2.2. For practical purposes, a configuration of AISI 302 steel rods was chosen due to its commercial availability, with dimensions specified in Table 2.2.

$$\delta_{max} = \frac{PL^3}{3EI} \quad (2.1)$$

$$I = \frac{\pi D^4}{64} \quad (2.2)$$

Table 2.2: Comparison between Wu & Shi (2022) model and custom test model

Parameter	Wu & Shi model [6]	Custom test model
Maximum length	~ 860 mm	~ 450 mm
Minimum length	~ 400 mm	~ 250 mm
Diameters of constraints	[90, 80, 70, 60] mm	[55, 50, 45] mm
Base constraint diameter	100 mm	70 mm
Number of sections	2	2
Number of rods	6	6
Rod cross-section diameter	3 mm	0.8 mm
Rod material	Fiberglass	AISI 302

Despite steel's higher Young's modulus and the necessity for shorter rods with significantly smaller radii, we achieved greater deflections under the same load

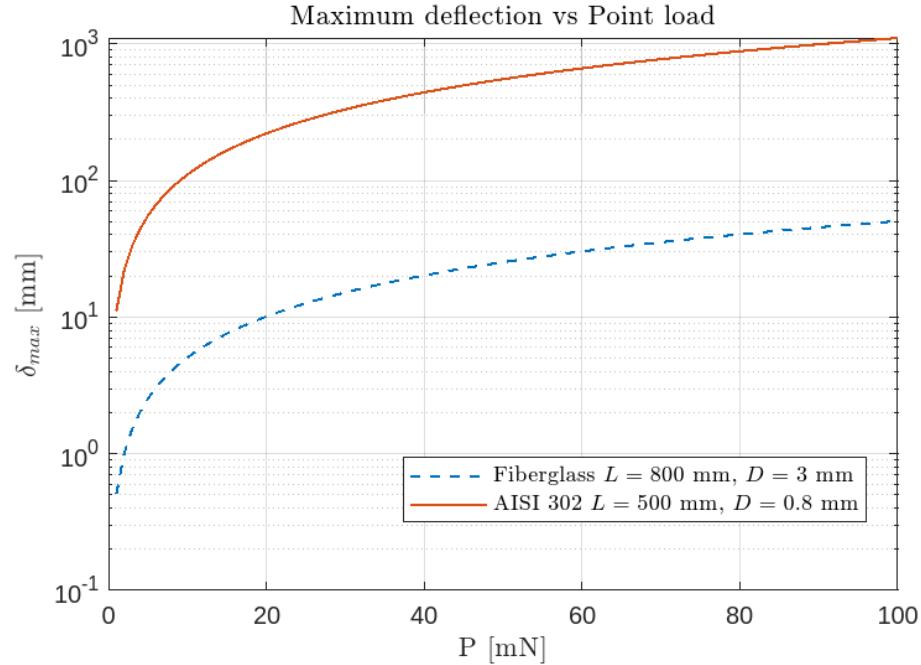


Figure 2.3: Maximum deflection and point load

compared to the reference model. This implies achieving equivalent deflection with less force, which is advantageous for actuators with limited force capabilities, as shown in Figure 2.3.

2.3 Design and Dimensions

To discuss the design and dimensions of the robot, the parts of the robot are depicted in Figure 2.4. These include rods for the first and second segments, constraints, and joints between constraints and rods, which can be either closed-form or cylindrical-form pairs designed to restrict movement. Each intermediate segment is required to have at least one closed-form pair joint with a rod for structural stability, while the remaining joints should be cylindrical to facilitate bending of the arm. At the end of each segment, all joints within the constraints must be closed-form to prevent disassembly of the segment. A minimum of three rods per segment is necessary to maintain structural integrity.

In Figure 2.5, the height of each segment and their respective constraints are il-

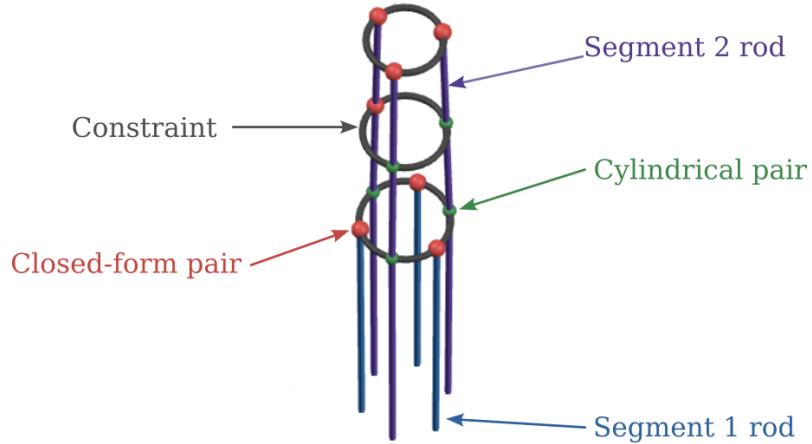
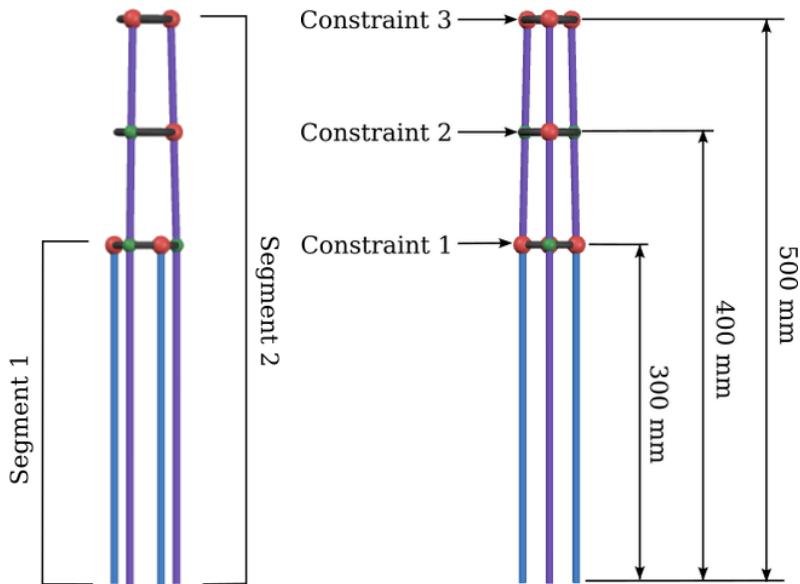


Figure 2.4: Robot body constraints and parts

lustrated. Additionally, the arm, similar to the reference model, exhibits a tapered envelope. This design choice, influenced by Wu and Shi [6], enhances structural stiffness. The tapered shape, resembling a truncated cone, is achieved by gradually reducing the cross-sectional area along the length of the arm, contributing to improved rigidity.



(a). Left view, and robot (b). Frontal view, and constraints heights
body segments

Figure 2.5: Robot body lateral views

2.4 Ring Constraints

The proposed constraint design, depicted in Figure 2.6, takes the form of a ring or hoop and is specifically tailored for additive manufacturing. Its cross-sectional shape is crucial in enhancing lateral load-bearing capabilities by mitigating deformation under load. Unlike traditional circular profiles that can easily deform into ellipses, the chosen rhomboidal cross-section provides structural stability. This geometric configuration, resembling a hollowed-out egg-shaped cylinder in its cross-section, offers improved resistance to lateral forces, ensuring robust performance in rod-driven continuous parallel robots.

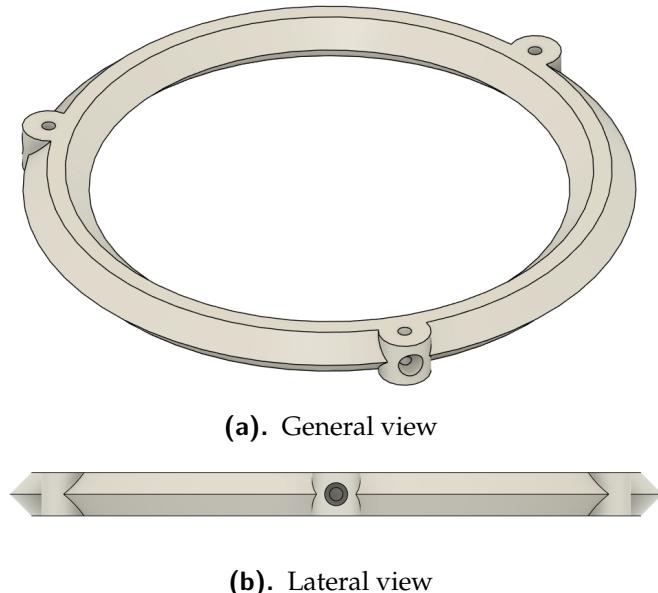
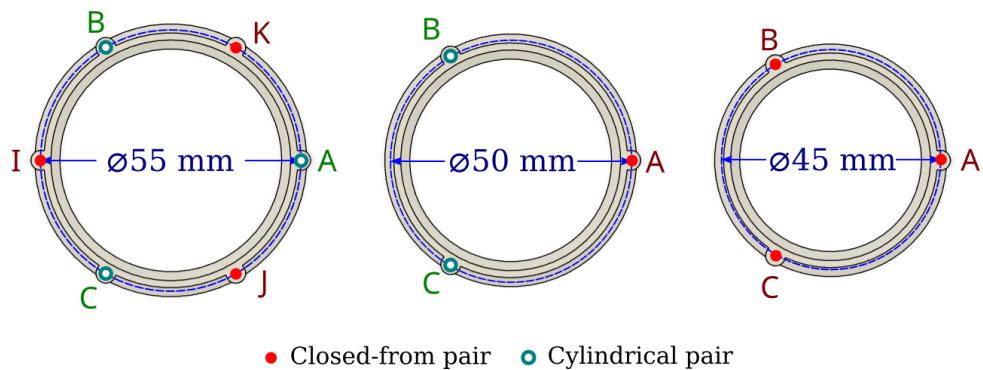


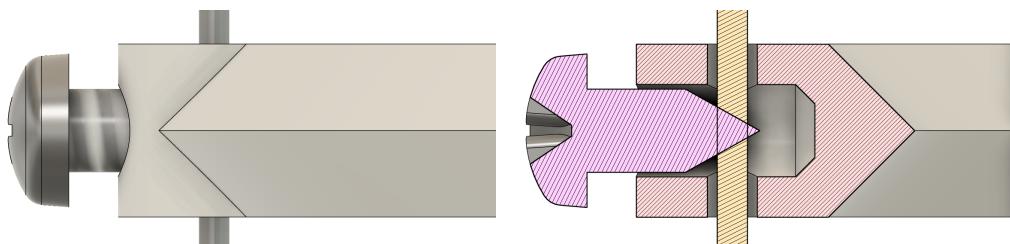
Figure 2.6: Ring constraint

The sizes of the constraints used in the rod-driven continuous parallel robots vary, as illustrated in Figure 2.7, corresponding to the dimensions specified in Table 2.2. Each constraint size is tailored to accommodate specific rod diameters, as indicated by the rod passing through each hole in the constraint. The type of connection with the constraint, whether closed-form or cylindrical, is also noted in the image.

**Figure 2.7:** Ring constraint sizes

In *blue*, the diameters of the circumferences enclosing the rods are shown. The rods are labeled *A*, *B*, *C*, *I*, *J*, *K*. The *green* open circle indicates a cylindrical pair constraint between the ring and the rod, while the *red* indicates a closed-form pair constraint involving both.

Physically, a closed-form pair joint is created using a set screw that secures the rod in place, as illustrated in Figure 2.8. This type of joint provides a firm grip on the rod, preventing any movement. In contrast, a cylindrical-form pair joint is similar in construction but omits the set screw, allowing for both translational and rotational movement along the axis of the hole.



(a). Physical closed-form pair constraint (b). Section view of closed-form pair constraint

Figure 2.8: Closed-form pair constraint

Chapter 3

Linear Actuator

Actuators play a crucial role in the operation of robots by converting the rotational movement of a motor into linear motion, enabling the robot to perform various tasks. In the context of parallel robots, linear actuators are particularly important because they are responsible for the movements needed to control the robot's motion.

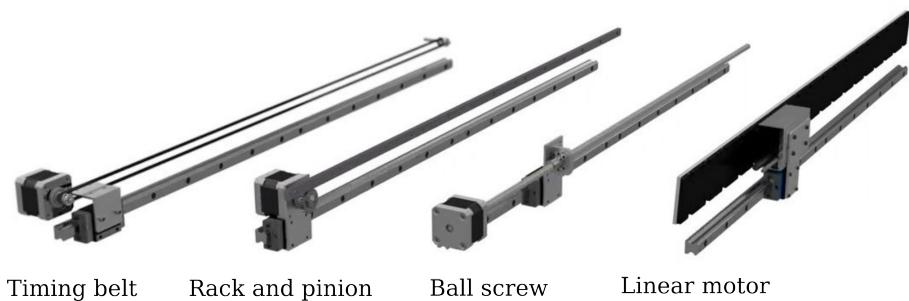


Figure 3.1: Linear motion systems

In parallel robots, linear actuators are used to manipulate the position and orientation of the end-effector. Traditional linear actuators include timing belts, rack and pinion systems, ball screws, and linear motors, as shown in Figure 3.1. However, these actuators often present challenges such as high cost, large size, and fixed or non-modifiable maximum stroke lengths.

The fixed or non-modifiable travel distance of conventional linear actuators is a major limitation, especially when the goal is to create a flexible platform capable of accommodating a wide range of rod-driven robot configurations. Flexibility is key to our platform, as it must adapt to various setups without requiring significant modifications.

Fortunately, parallel continuum robots open up a broader range of possibilities. Unlike traditional robots that move rigid elements, continuum robots use flexible elements like rods, which can be shortened or extended to achieve the desired motion. This concept is similar to the operation of 3D printer extruders (refer to Figure 3.2).

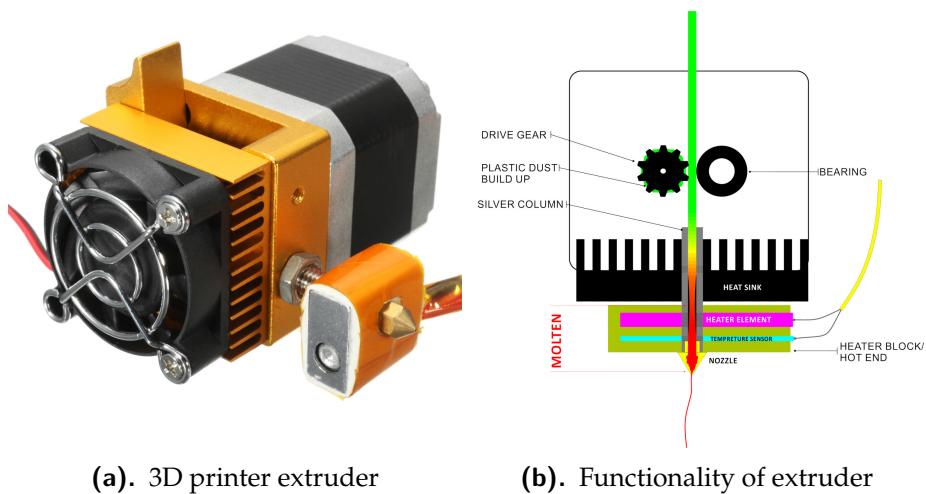


Figure 3.2: 3D printer extruder

3D printer extruders work by using a drive gear and a bearing to push and pull the filament towards the heater. For our application, we are not interested in the heating aspect but rather the mechanism that drives the filament. This mechanism can be adapted to move rods in our robot, as shown in Figure 3.3.



Figure 3.3: Extruder without heater

A custom design is necessary for several reasons. The filaments used in standard extruders are thicker than the rods suitable for our robots (> 1.75 mm), as empirical experience suggests that rods thinner than 1.5 mm are ideal. Thicker rods require more force to bend, which these actuators are not designed to handle, making this thickness a practical upper limit for our application. Additionally, the width of the actuators must be considered, along with their weight and speed. Energy consumption is also a critical factor that must be taken into account.

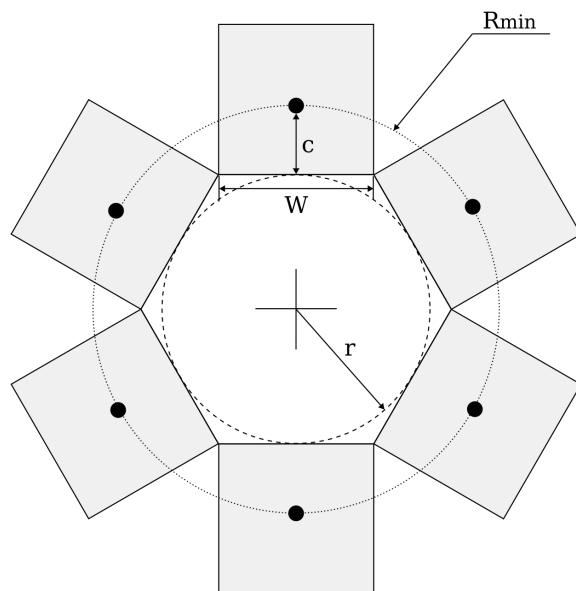


Figure 3.4: Actuators arrange

Each rod requires its own actuator. Therefore, the actuators must fit within the stipulated diameter for the base of the arm. The top view of an actuator arrangement is shown in Figure 3.4. For an arrangement of six actuators with width W and distance to the center c , the relationship with the minimum base radius R_{min} is shown in equations 3.2 and 3.1. An original extruder has a width of $W = 5.2$ cm with $c = 0.7$ cm, which requires a minimum radius of $R_{min} = 5.2$ cm according to equation 3.4. This is larger than the model presented by [6], and our aim is to design a smaller one. Therefore, we establish a minimum diameter of $R_{min} = 3.5$ cm with a maximum $c = 0.5$ cm, resulting in a maximum width of $W \approx 3.5$ cm, according to equation 3.3.

$$r = R_{min} - c \quad (3.1)$$

$$W = \frac{2}{\sqrt{3}}r \quad (3.2)$$

$$W = \frac{2}{\sqrt{3}}(R_{min} - c) \quad (3.3)$$

$$R_{min} = \frac{\sqrt{3}}{2}W + c \quad (3.4)$$

3.1 Motor

The motor is the central component in actuators, and in extruders, stepper motors are commonly used. However, stepper motors were discarded for our application due to their size and speed limitations. Instead, we selected DC N20 geared motors, which are small and fast enough to meet our requirements. To control the number of revolutions accurately, a motor with an encoder is necessary (see Figure 3.5). The dimensions of the selected motor with encoder are specified in Figure 3.6, and the specifications for the chosen variant are detailed in Table 3.1.



Figure 3.5: Gear motor N20 with encoder

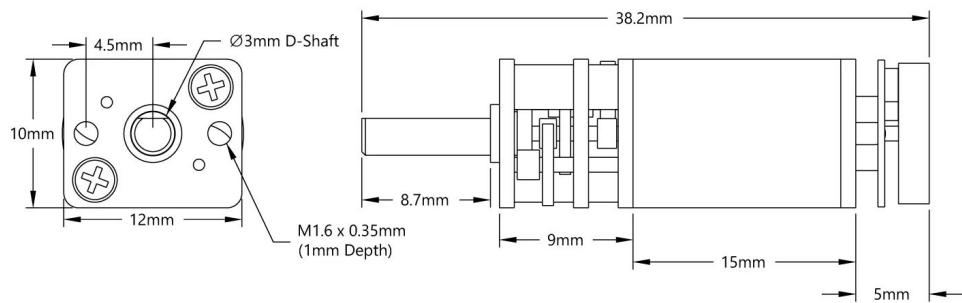


Figure 3.6: Dimensions of gear motor N20 with encoder

Table 3.1: Gear motor specifications

Property	Value
Output shaft style	D-Shaft
Voltage range	6 – 12V
Speed (no load @ 6VDC)	70 rpm
Rated torque	0.65 kg·cm
Stall torque	4 kg·cm
Gear ratio	210:1
Weight	15g
Encoder: cycles per revolution (motor shaft)	3
Encoder sensor type	Magnetic (Hall Effect)
Hall response frequency	100 kHz

3.2 First model

A first concept of the linear actuator is shown in Figure 3.7. This simple and straightforward model was designed to understand the basic concept of a linear actuator. The idea was to make it easy to manufacture using FDM (fused deposition modeling), specifically 3D printing. The width of this model is 46.06 mm (as shown in Figure 3.8), which exceeds the previously stipulated 35 mm. We found limitations when trying to reduce the actuator's width due to the diameters of the pulley, bearing, spring, and the length of the arm. Additionally, the bearing did not provide sufficient friction, necessitating improvements in this area. Enhancements were also needed for the motor grip and support to ensure ease of printing and overall functionality.

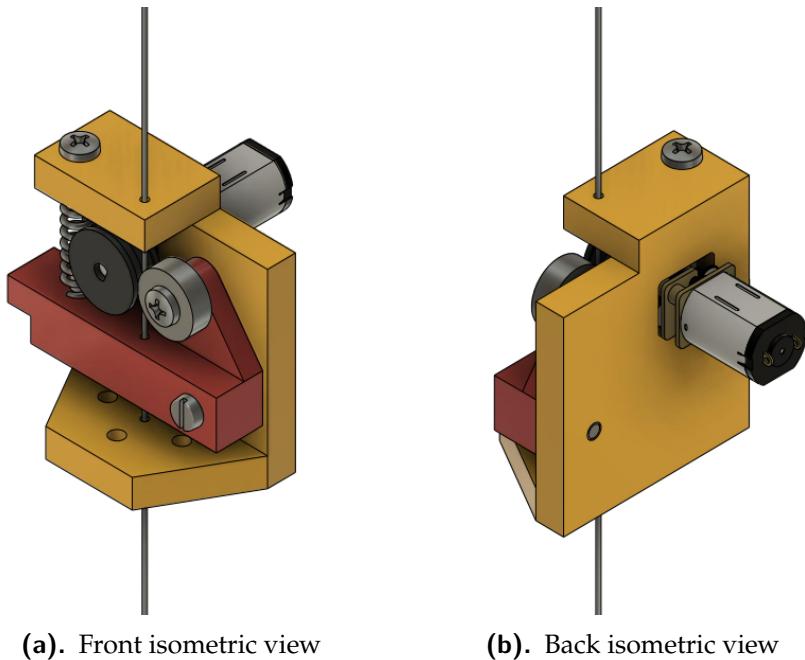
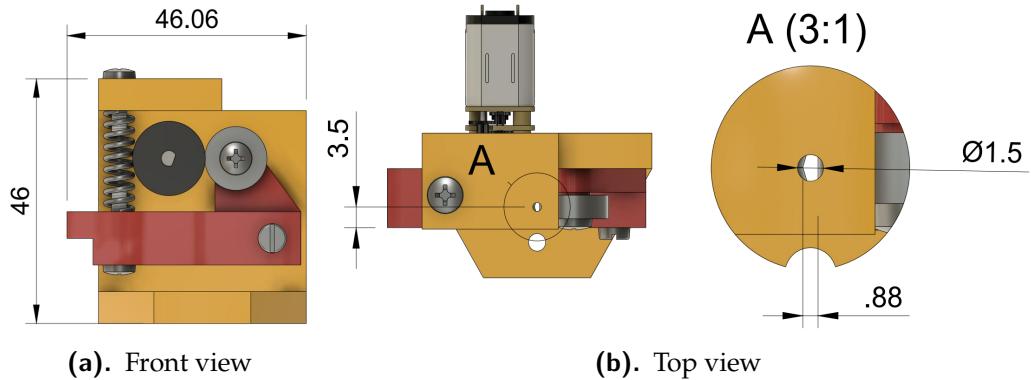
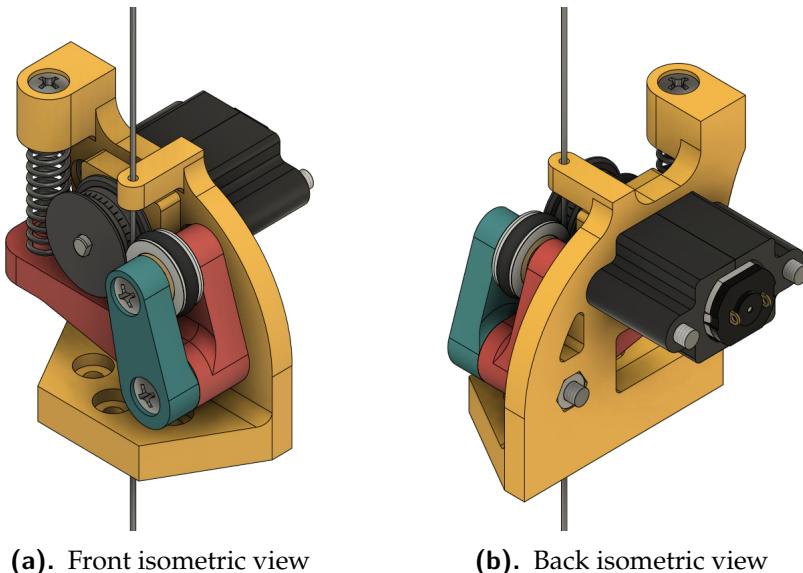


Figure 3.7: First model isometric view

**Figure 3.8:** First model dimensions

3.3 Final model

After some iterations, the final model was developed, as shown in Figure 3.9. The final design is more rounded to eliminate potential stress concentrators, and it is also more streamlined and material-efficient, incorporating holes in non-critical areas to reduce weight.

**Figure 3.9:** Final model isometric view

Although the width remains the same, the arm, which previously collided with other actuators in an array, has been repositioned. It is now slightly shorter

and rounded, as shown in Figure 3.10, allowing the arm to intrude into the space of another actuator without making contact at any point. This design maintains an array of 6 actuators within the established circle diameter of 7 cm.

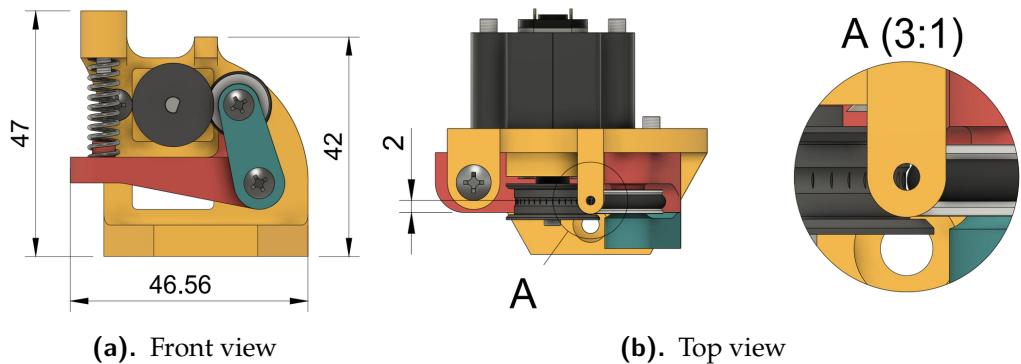
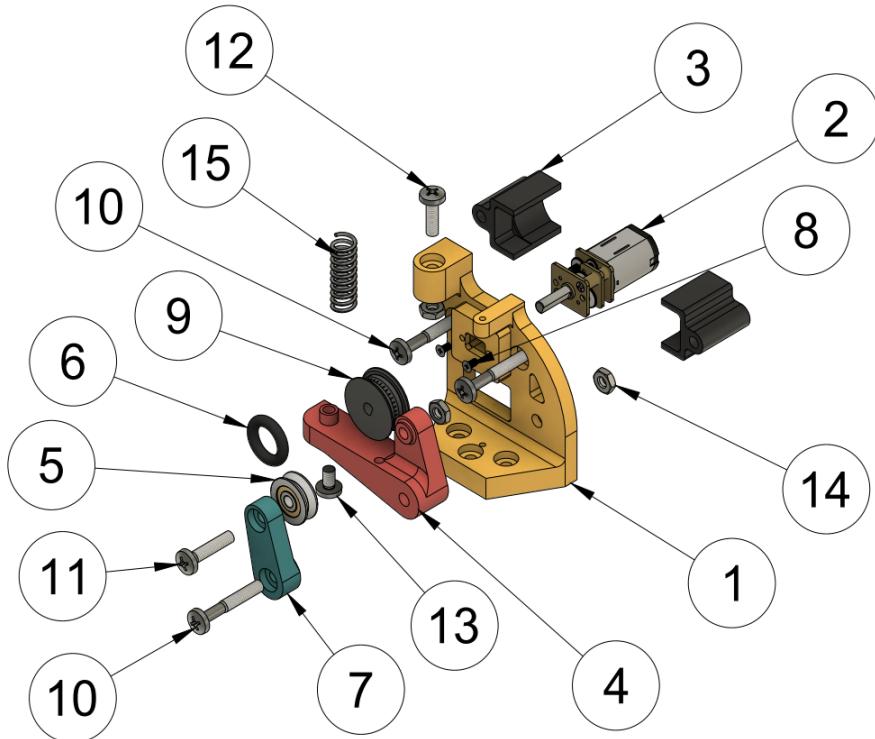


Figure 3.10: Final model dimensions

The issue of friction was also addressed by adding an O-ring seal in a V-shaped bearing and creating a grooved pattern on the motor pulley. The space between the pulley was made narrower to enhance grip. Additionally, a pair of new components were designed to secure the motor, and an additional support was included over the arm and bearing for increased rigidity and safety. Critical parts such as the spring holder were reinforced, making them thicker to improve durability and performance.

Figure 3.11 presents an exploded view of the final actuator, detailing each component with arrows and item numbers in balloons. The corresponding part names for the assembly are listed in Table 3.2, which also indicates the quantity and source of each part. The sources are categorized as 3D printed, commercial, or manufactured. Notably, the only "manufactured" part is the spring, which was custom-made.

**Figure 3.11:** Actuator assembly exploded-view**Table 3.2:** Actuator assembly parts list

Item	Qty	Part Name / Description	Source
1	1	Base	3D Printed
2	1	Motor GA12 N20 (must be with encoder)	Commercial
3	2	Motor Support	3D Printed
4	1	Arm	3D printed
5	1	V623ZZ Groove Pulley	Commercial
6	1	O-Ring - W2.62 x DI7.59 x DE2.83	Commercial
7	1	Arm Support	3D Printed
8	2	Phillips Countersunk Screw - DIN 965H M1.6x3	Commercial
9	1	Pulley	3D Printed
10	3	Binding Head Screw JIS B 1111 - M3x20	Commercial
11	1	Binding Head Screw JIS B 1111 - M3x14	Commercial
12	1	Binding Head Screw JIS B 1111 - M3x10	Commercial
13	1	Binding Head Screw JIS B 1111 - M3x5	Commercial
14	3	Hexagon Thin Nut DIN 439-2 - M3x0.5	Commercial
15	1	Spring - D5.5x20mm	Manufactured

3.4 Specifications

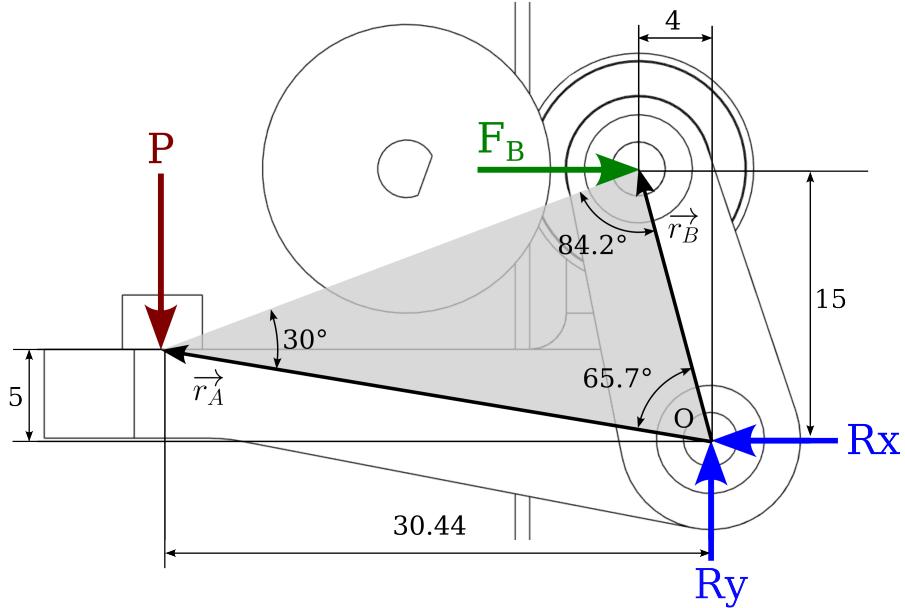


Figure 3.12: Forces in actuator arm

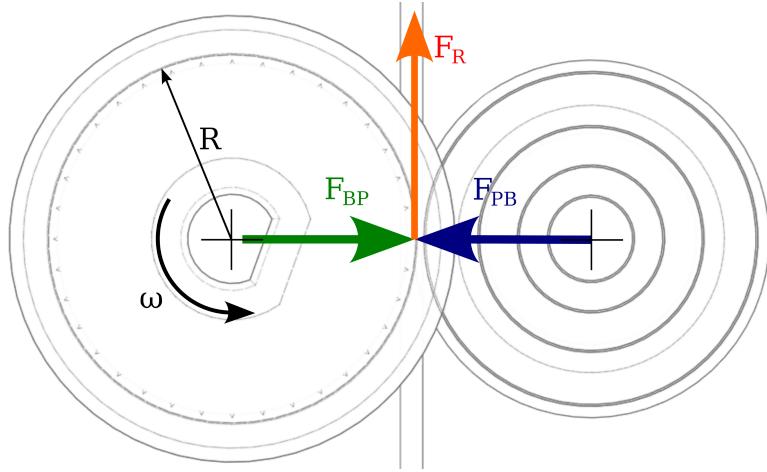
The pressure or grip on the rod by the actuator is provided by the bearing and the actuator arm, whose static model is shown in Figure 3.12. The sum of forces is found in Equation 3.5, and the sum of moments at point O is given in Equation 3.6. The force P is exerted by the spring, as described by Equation 3.7, where k is the spring constant and Δy is the compression. At the pin O , the components of the reaction force, R_x and R_y , are present. From Equation 3.6, we can determine the reaction force F_B at the bearing, as shown in Equation 3.8.

$$\sum \vec{F} = 0 \quad \therefore \quad \vec{P} + \vec{R}_y + \vec{F}_B + \vec{R}_x = 0 \quad (3.5)$$

$$\sum \vec{M}_O = 0 \quad \therefore \quad \vec{r}_A \times \vec{P} + \vec{r}_B \times \vec{F}_B = 0 \quad (3.6)$$

$$P = -k\Delta y \quad (3.7)$$

$$F_B = \frac{r_{A,x}}{r_{B,y}} P = \frac{30.44}{15} P = -2.0293 k \Delta y \quad (3.8)$$

**Figure 3.13:** Friction force in rod

From the force F_B , the friction force on the rod can be calculated, as shown in Figure 3.13, using Equation 3.10. However, these formulas were not applied in depth because static friction factors of the robot μ_s were measured instead. Geometric constraints were of greater importance. Therefore, the spring was selected by empirically testing those with the appropriate stiffness. The drive pulley, with radius R , rotates at speed ω . Considering the motor's RPM, the actuator's speed specifications are provided in Table 3.3.

$$F_{BP} = F_B \quad (3.9)$$

$$F_R = \mu_s F_{BP} = -2.0293\mu_s k \Delta y \quad (3.10)$$

Table 3.3: Actuator specification

Property	Value
Pulley ratio (R)	5.3 mm
Maximum angular velocity (ω_{max})	7.3304 rad/s
Maximum linear velocity (v_{max})	38.85 mm/s

Chapter 4

Platform Assembly

4.1 Electronics Case

4.1.1 Circuit Schematic

Table 4.1: Platform assembly parts list

Item	Qty	Part Name / Description	Source
1	1	Actuators Base	3D Printed
2	2	Support Base	Acrylic Laser Cut
3	6	Support Union	Acrylic Laser Cut
4	1	Support Front	Acrylic Laser Cut
5	2	Support Lateral	Acrylic Laser Cut
6	1	Electronics Assembly	
7	4	Binding Head Screw JIS B 1111 - M3x40	Commercial
8	24	Binding Head Screw JIS B 1111 - M3x10	Commercial
9	6	Actuator Assembly	

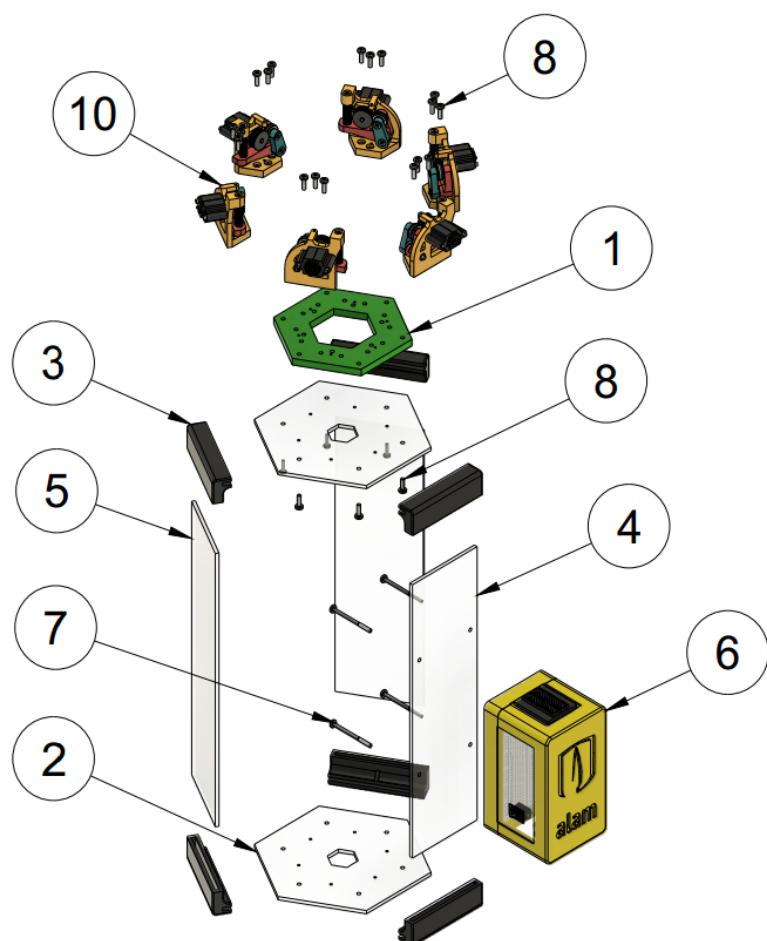


Figure 4.1: Platform assembly exploded-view

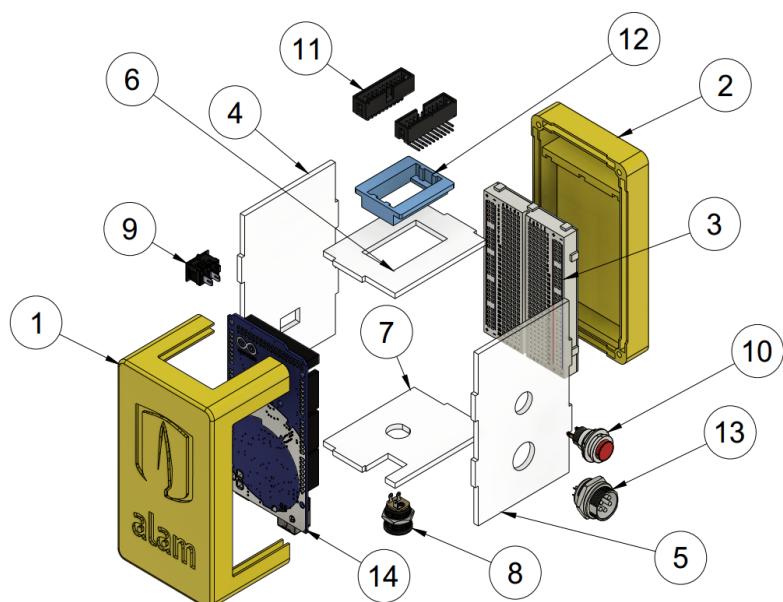
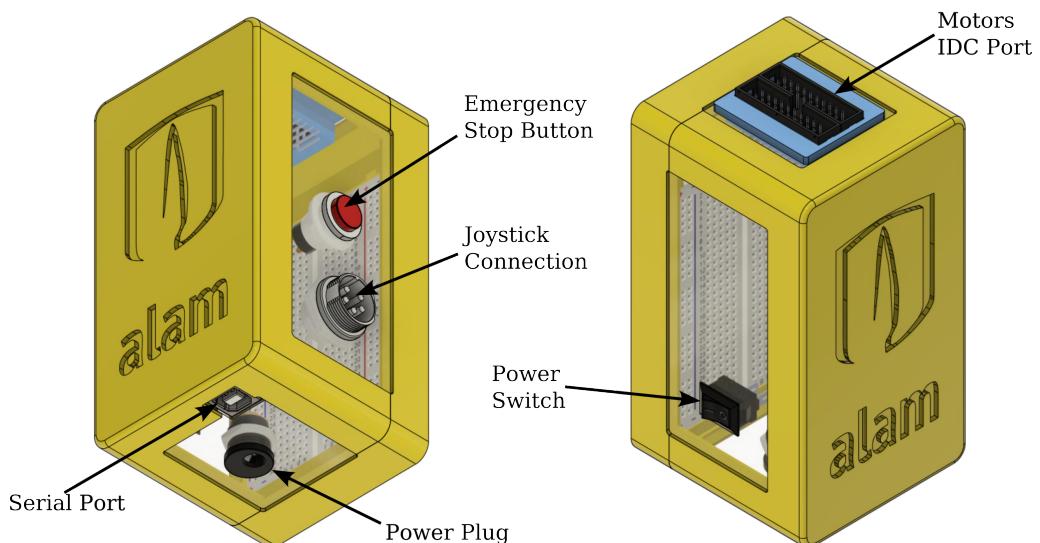


Figure 4.2: Electronics assembly exploded-view

Table 4.2: Electronics assembly parts list

Item	Qty	Part Name / Description	Source
1	1	Arduino Case	3D Printed
2	1	Breadboard Base	3D Printed
3	1	Half-Size Breadboard	Commercial
4	1	Left Wall	Acrylic Laser Cut
5	1	Right Wall	Acrylic Laser Cut
6	1	Top Wall	Acrylic Laser Cut
7	1	Bottom Wall	Acrylic Laser Cut
8	1	DC Power Input Jack - DS-223B	Commercial
9	1	Power Switch - KCD1-11-2P	Commercial
10	1	Red Push Button - DS 212	Commercial
11	2	IDC 3020-20-0200-00 - 20P 2.54MM	Commercial
12	1	IDC Support	3D Printed
13	1	MX M12 5-Pin Male MIC Connector Plug	Commercial
14	1	Arduino MEGA 2650	Commercial

**Figure 4.3:** Ports and connections

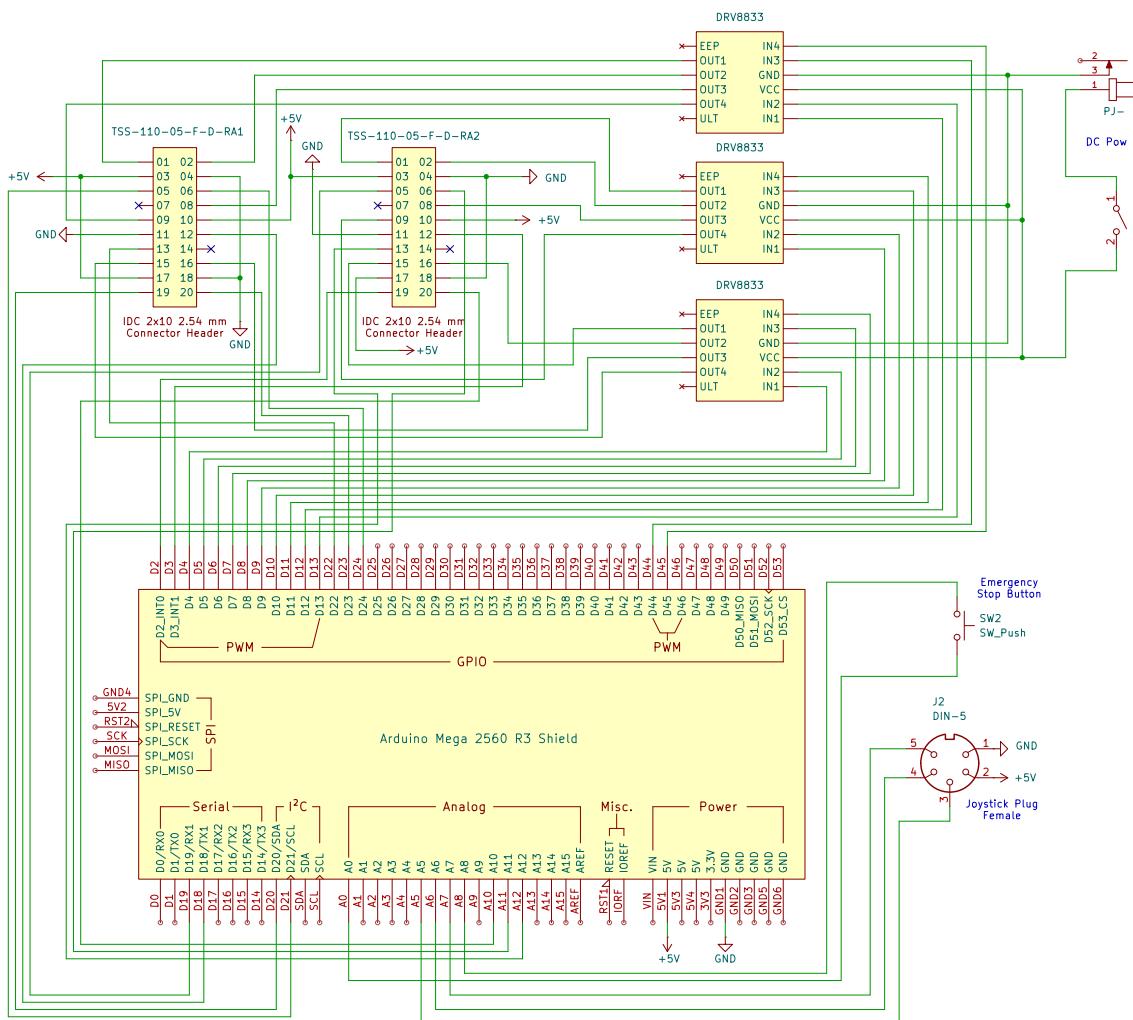


Figure 4.4: Main circuit schematic

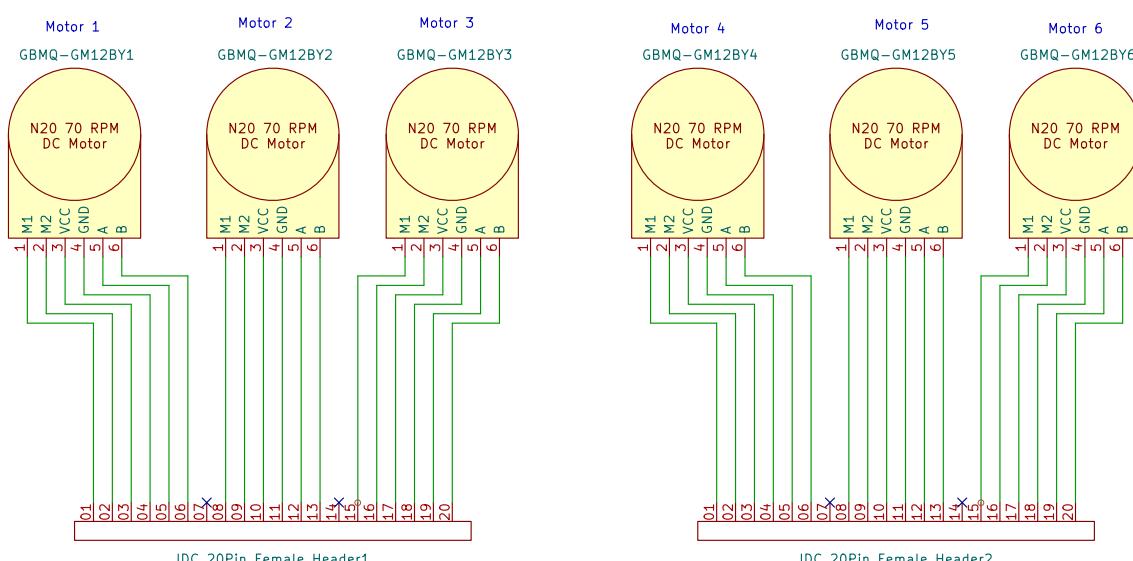


Figure 4.5: Motor circuit schematic

Chapter 5

Control System Interface

5.1 Protocol Specifications

Table 5.1: G-Code definitions

G-Code	Definition
G1	Move one or more actuators to specified positions at a given operational speed.
G4	Pause or dwell. Halts the machine for the specified duration.
G28	Move actuators to origin position.
G28.1	Move actuators to target position.
G90	Set absolute positioning mode. All subsequent movements are interpreted as absolute positions. This is the default mode.
G91	Set relative positioning mode. All subsequent movements are interpreted as displacements from the current position.
G92	Set origin position.
G92.1	Set target position. This may be a position of interest.

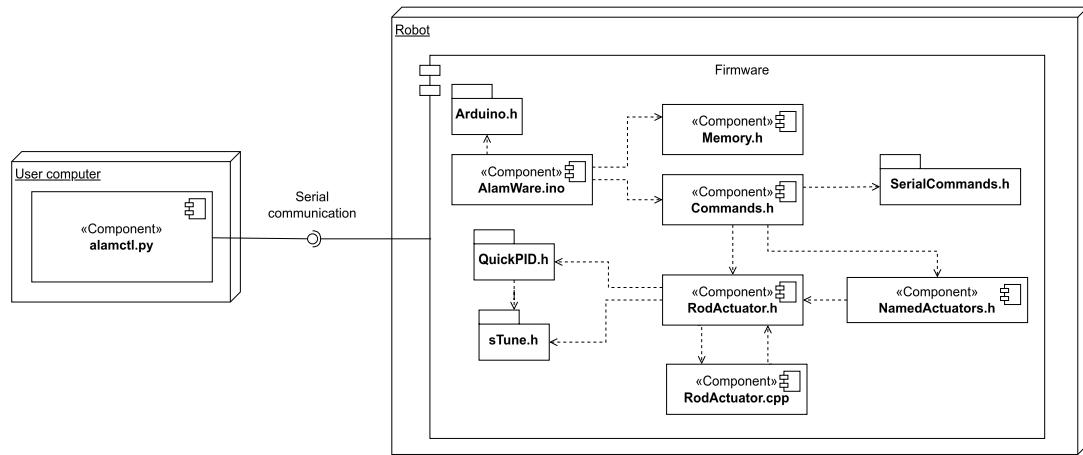


Figure 5.1: Relationships of control system components

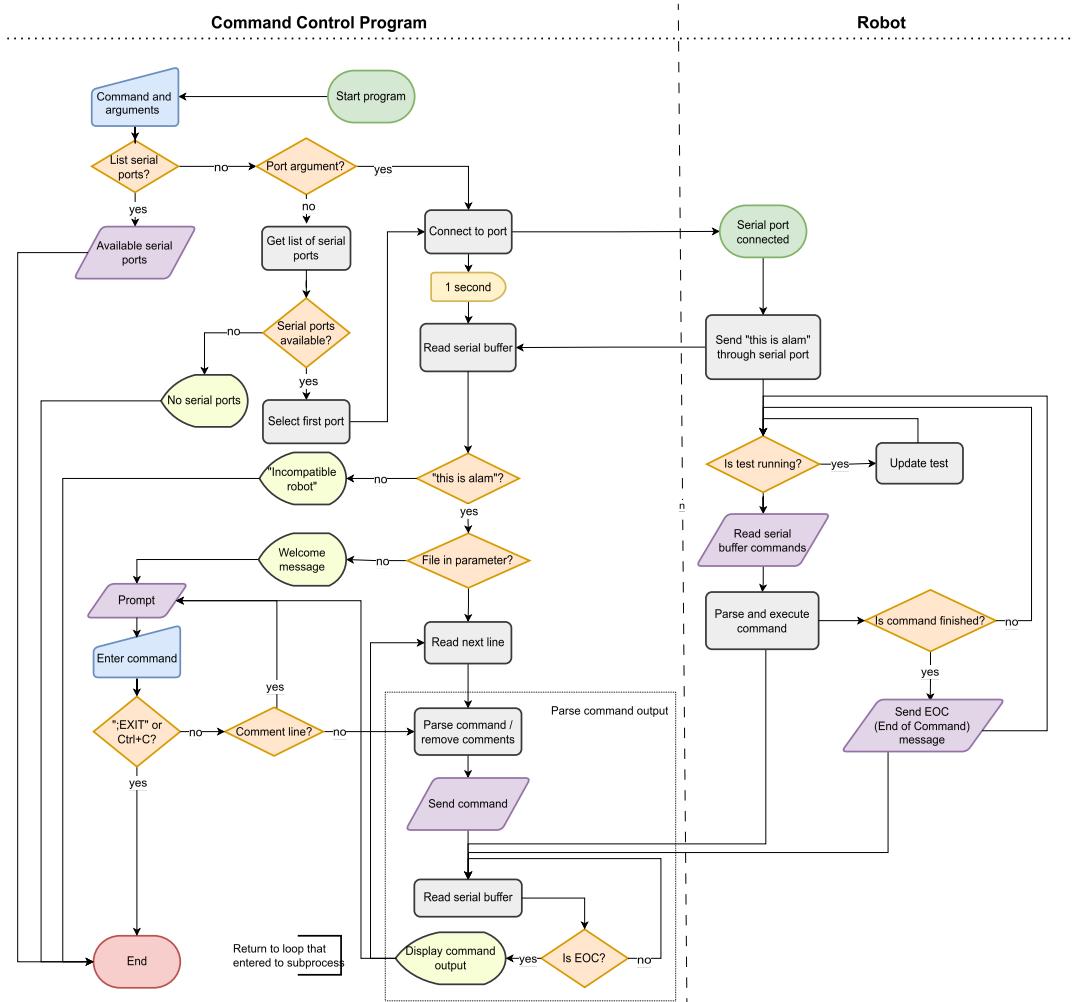
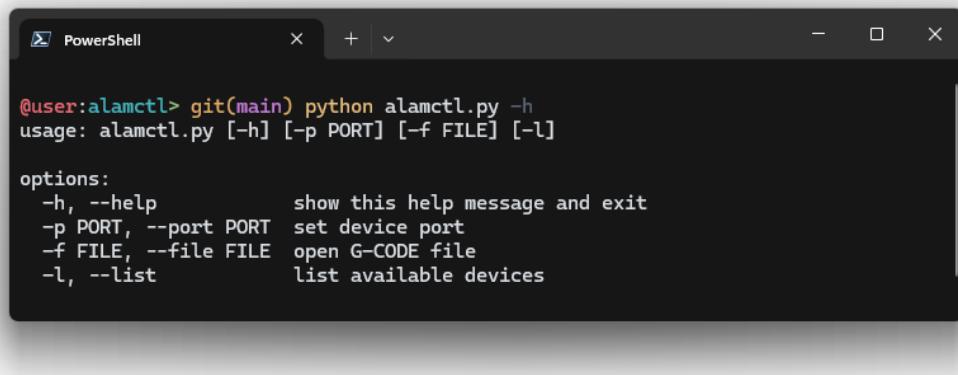


Figure 5.2: System flowchart

Table 5.2: M-Code definitions

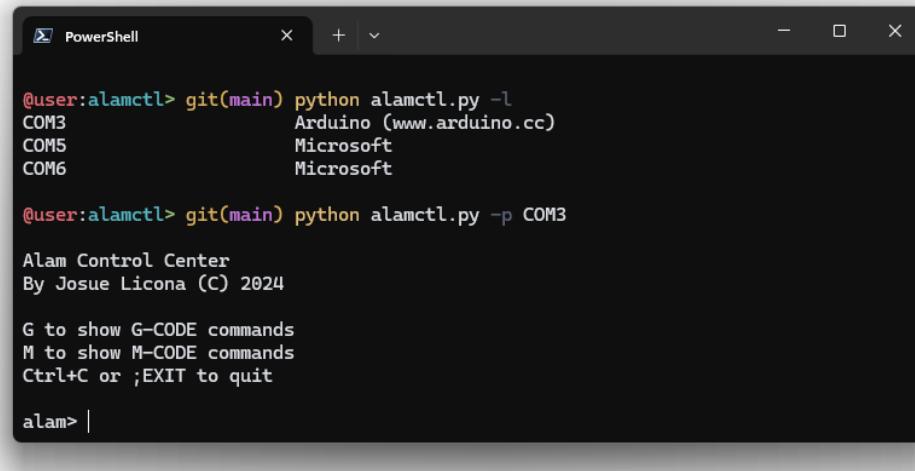
M-Code	Definition
M00	Stop program
M85	Maximum command wait time.
M114	Report current position of the actuators.
M301	Set PID parameters.
M303	Initiate autotuning process for the PID parameters.
M355	Report current status of robot parameters.
M500	Save parameters to EEPROM.
M501	Load parameters from EEPROM.
M502	Reset parameters saved in EEPROM to defaults.
M503	Display the saved configuration in EEPROM.



```
@user:alamctl> git(main) python alamctl.py -h
usage: alamctl.py [-h] [-p PORT] [-f FILE] [-l]

options:
-h, --help            show this help message and exit
-p PORT, --port PORT set device port
-f FILE, --file FILE  open G-CODE file
-l, --list             list available devices
```

Figure 5.3: Command line usage



```
@user:alamctl> git(main) python alamctl.py -l
COM3           Arduino (www.arduino.cc)
COM5           Microsoft
COM6           Microsoft

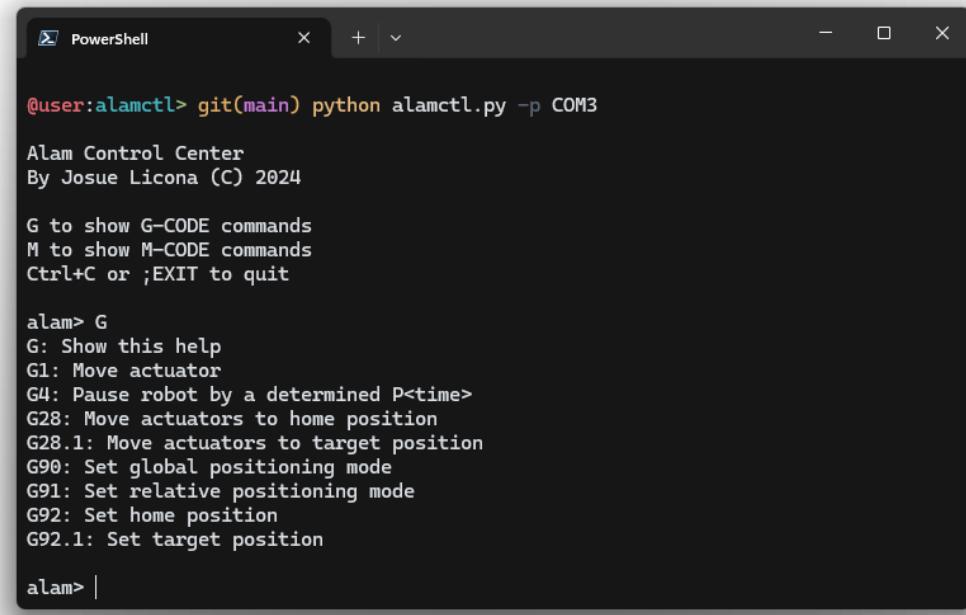
@user:alamctl> git(main) python alamctl.py -p COM3

Alam Control Center
By Josue Licona (C) 2024

G to show G-CODE commands
M to show M-CODE commands
Ctrl+C or ;EXIT to quit

alam> |
```

Figure 5.4: Command line connection



```
@user:alamctl> git(main) python alamctl.py -p COM3

Alam Control Center
By Josue Licona (C) 2024

G to show G-CODE commands
M to show M-CODE commands
Ctrl+C or ;EXIT to quit

alam> G
G: Show this help
G1: Move actuator
G4: Pause robot by a determined P<time>
G28: Move actuators to home position
G28.1: Move actuators to target position
G90: Set global positioning mode
G91: Set relative positioning mode
G92: Set home position
G92.1: Set target position

alam> |
```

Figure 5.5: Command line manual input

Table 5.3: G-Codes usage

Code	Usage	Example
G1	G1 <id><pos> [F<speed,255>]	> G1 A100.0
G4	G4 P<millis> S<secs>	> G4 P3000
G20	G20	> G20
G21	G21	> G21
G28	G28 [<id,A B C I J K>]	> G28 A B C
G28	G28.1 [<id,A B C I J K>]	> G28.1 J K
G90	G90	> G90
G91	G91	> G91
G92	G92 [<id,A B C I J K><pos,0>]	> G92 A-100.0 I5.0
G92.1	G92.1 [<id, A B C I J K><pos,0>]	> G92.1 B250.0

5.2 Command Line Application

5.2.1 Architecture

5.2.2 Usage

5.3 PID Control and Tuning

5.3.1 Test Data

5.3.2 System Identification

$$tf = \frac{(4.808 - 4.596z^{-1}) \times 10^{-4}}{1 - 1.982z^{-1} + 0.9824z^{-2}} \quad (5.1)$$

5.3.3 PID Tuning

$$C = Kp + Ki * \frac{Ts}{z - 1} \quad (5.2)$$

Table 5.4: M-Codes usage

Note that only commands with parameters are explained. All others can be used by simply entering the code.

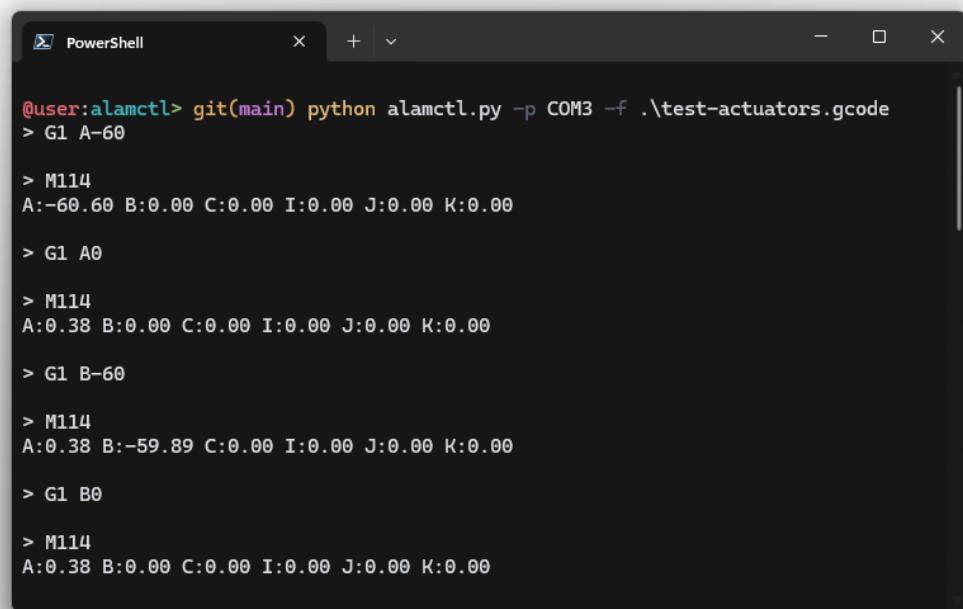
Code	Usage	Example
M85	M85 P<millis,5000> S<secs,5>	> M85 S3
M301	M301 [P<kp,0>] [I<ki,0>] [D<kd,0>]	> M301 P1000 I0.5
M500	M500 <optn>	> M500 T P
M502	M502 <optn>	> M502 I J K

Table 5.5: Code parameters

Parameter	Meaning
<id>	Actuator identification letter: A, B, C, I, J or K.
<pos>	Position number.
<kp>	Proportional constant.
<ki>	Integral constant.
<kd>	Derivative constant.
<speed>	Maximum speed of actuator as integer number from 50 to 255.
<millis>	Milliseconds as integer number.
<secs>	Seconds as integer number.
<optn>	Parameter of the robot. T for PID tuning constants; A, B, C, I, J or K for position of given actuator; P for all actuator positions
<..., VALUE>	Default value.
[...]	Optional parameter. If omitted, default value will be used.

Table 5.6: PID Tunings

Property	Value
Proportional constant, K_p	21.4
Integrative constant, K_i	1.97
Sample time, T_s	0.00381s



```
@user:alamctl> git(main) python alamctl.py -p COM3 -f .\test-actuators.gcode
> G1 A-60

> M114
A:-60.60 B:0.00 C:0.00 I:0.00 J:0.00 K:0.00

> G1 A0

> M114
A:0.38 B:0.00 C:0.00 I:0.00 J:0.00 K:0.00

> G1 B-60

> M114
A:0.38 B:-59.89 C:0.00 I:0.00 J:0.00 K:0.00

> G1 B0

> M114
A:0.38 B:0.00 C:0.00 I:0.00 J:0.00 K:0.00
```

Figure 5.6: Command line file parsing

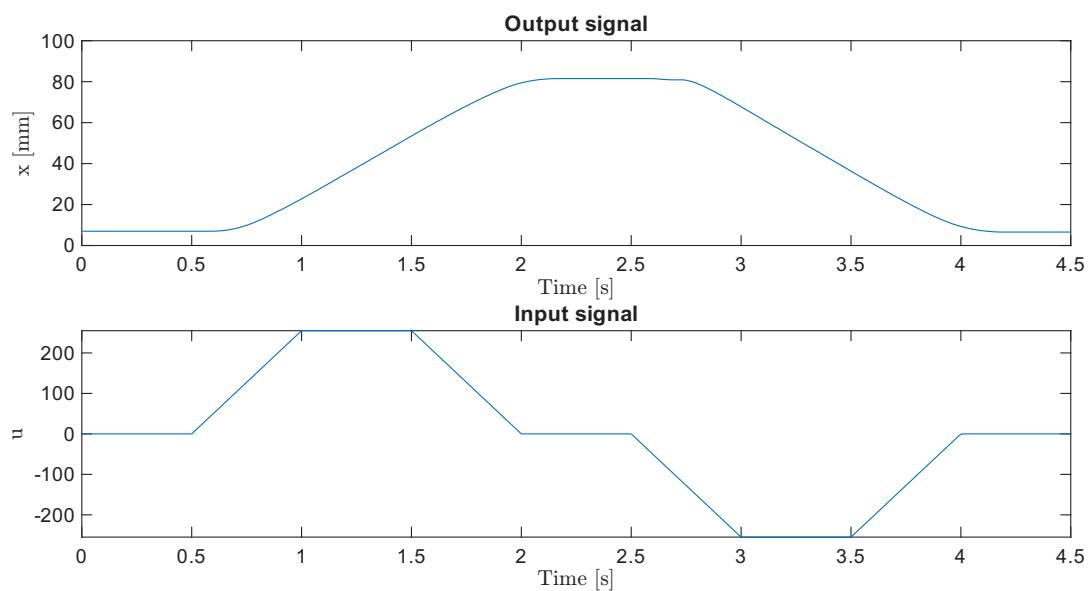


Figure 5.7: Input and output signals

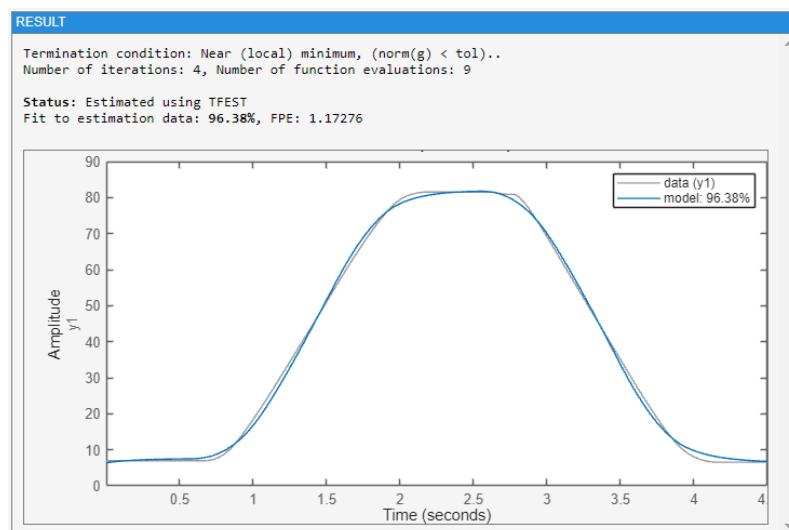
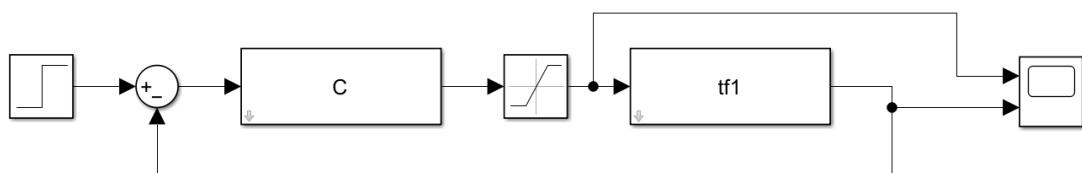
```

Transfer Function Identification
Estimation data: Time domain data mydata
Data has 1 outputs, 1 inputs and 1181 samples.
Number of poles: 2, Number of zeros: 1

ESTIMATION PROGRESS

Initializing model parameters...
Initializing using 'arx' method...
Initialization complete.

Algorithm: Nonlinear least squares with automatically chosen line search method
-----
Iteration      Cost       Norm of   First-order  Improvement (%)
           step    optimality    Expected   Achieved   Bisectons
-----
0        2.23946      -     1.25e+09      50.7      -      -
1        1.97743  0.0168  2.19e+09      50.7     11.7      0
2        1.20415  0.00619  3.67e+08      44.3     39.1      0
3        1.16975  0.000536  6.76e+06      2.87     2.86      0
4        1.16971  0.000112  2.77e+05     0.00473   0.00377      0
-----
```

Figure 5.8: Transfer function identification in MATLAB**Figure 5.9:** Transfer function model in MATLAB**Figure 5.10:** Blocks diagram of control system

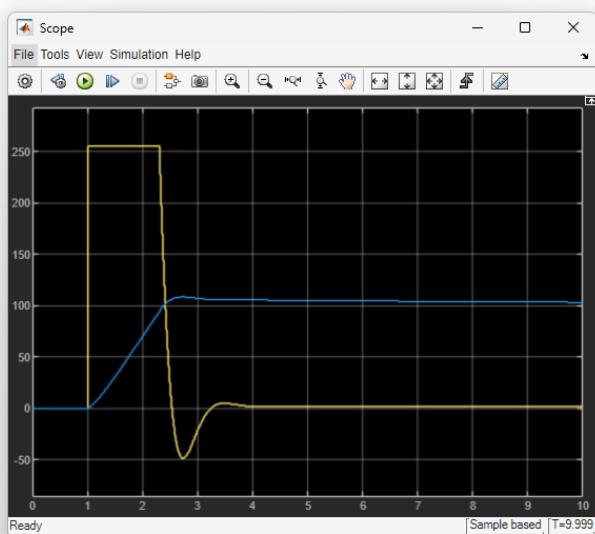


Figure 5.11: System response of simulation in Simulink

Chapter 6

Performance and Results

Table 6.1: Platform specifications

Property	Value
Height	30 cm
Maximum height (with arm)	70 cm
Weight	1 kg
Linear actuators tolerance	± 1 mm

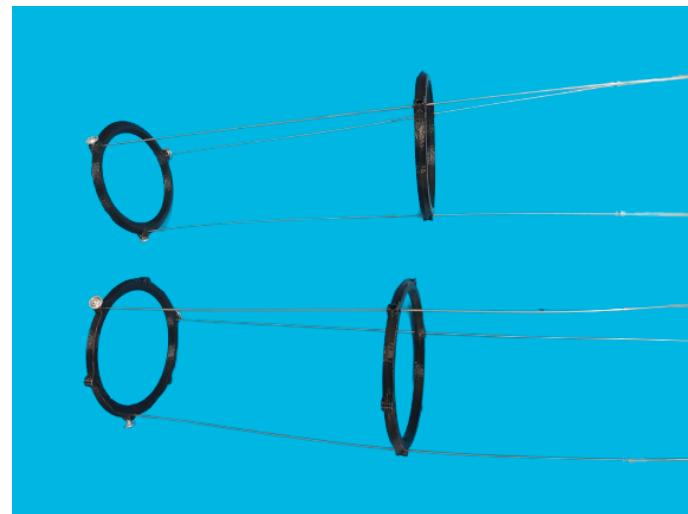
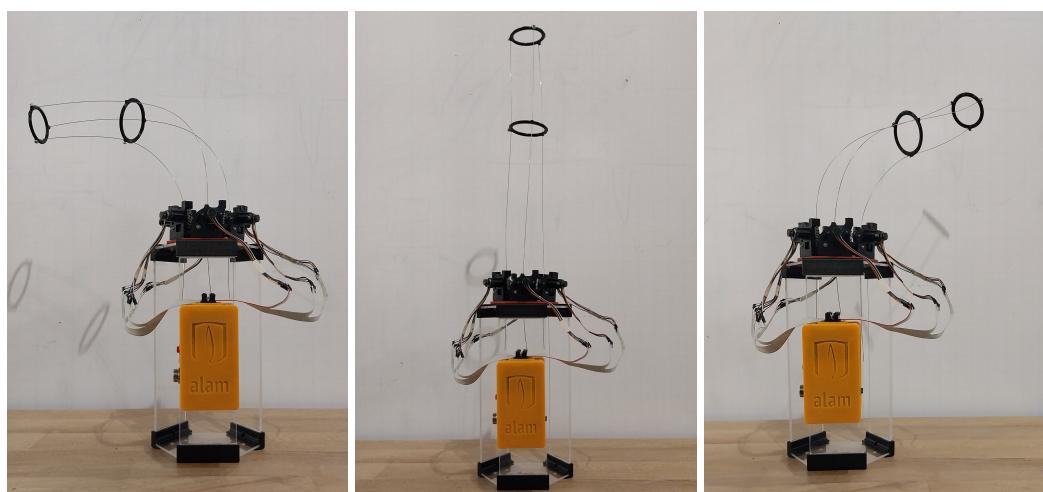


Figure 6.1: Arm segments



(a). Arm to the left

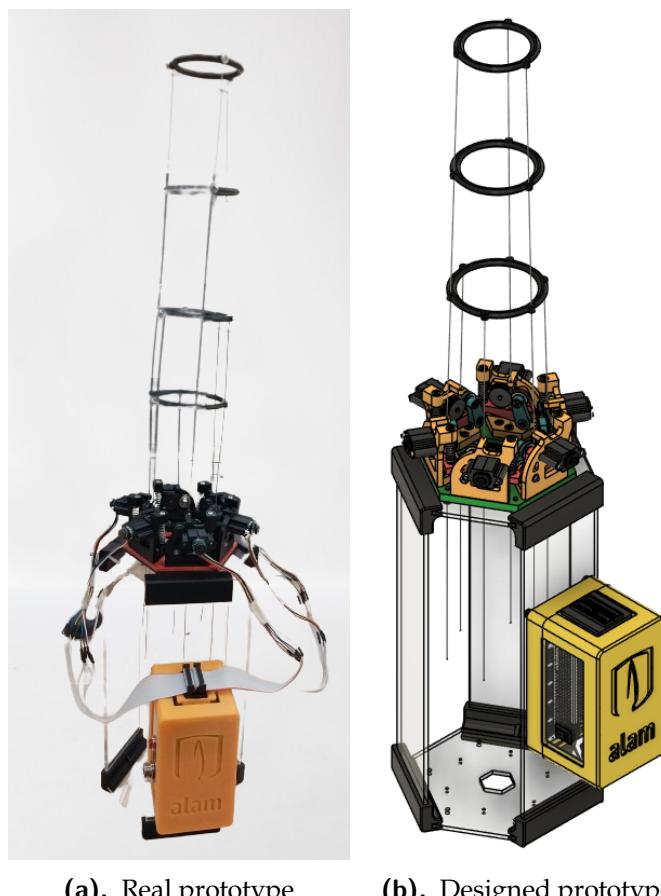
(b). Straight arm

(c). Arm to the right

Figure 6.2: One segment arm positions



Figure 6.3: Electronics case and connections



(a). Real prototype (b). Designed prototype

Figure 6.4: Complete prototype

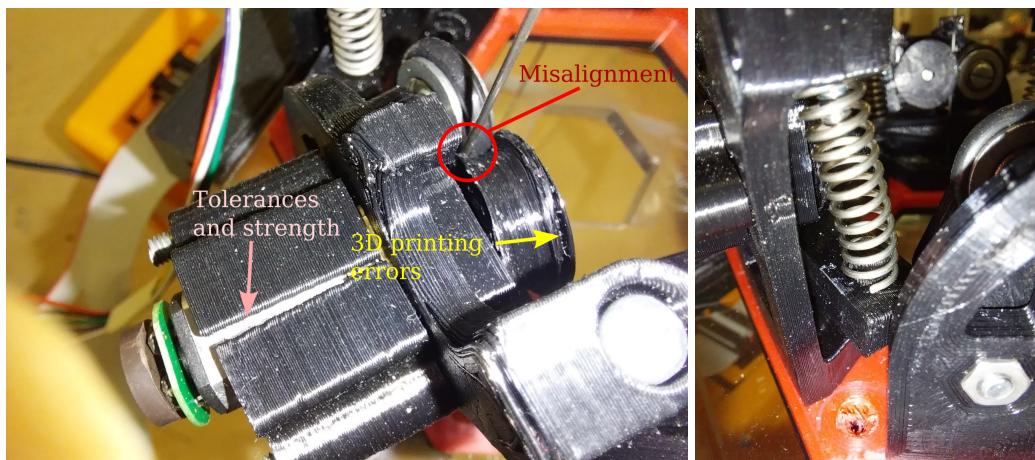


Figure 6.5: Linear actuator issues

Conclusions

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like "Huardest gefburn"? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like "Huardest gefburn"? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

Future Work and Recommendations

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like "Huardest gefburn"? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

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ference on Robotics and Automation (ICRA), 2017, pp. 6142–6149. doi: 10.1109/ICRA.2017.7989728.

Appendices

A Forces in Actuator Arm

```

syms Fb P rAx rAy rBx rBy

vecFb = [Fb 0 0];
vecP = [0 P 0];
rA = [rAx rAy 0];
rB = [rBx rBy 0];

eq = cross(rA, vecP) + cross(rB, vecFb);
solve(eq, Fb)

```

B PID Tuning Code

```

% Get data
dataTable = readtable("datos.csv");
t = dataTable.t/1000; %convert time from milliseconds to seconds
PWM = dataTable.PWM;
A = dataTable.A;
startTime = t(1);
sampleTime = mean(diff(t));
mydata = iddata(A,PWM,sampleTime, "Tstart", startTime);

% Find transfer function of system
npoles = 2; nzeros = 1;
Options = tfestOptions;
Options.Display = 'on';
Options.EnforceStability = true;
tf1 = tfest(mydata, npoles, nzeros, Options, 'Ts', sampleTime, ...
    'Feedthrough', true);

% PID Tune
opts = pidtuneOptions("PhaseMargin", 90);
[C, info] = pidtune(tf1, 'PI', 5, opts);

```

C Test Code

```
; ALAM ROBOT TEST
;BY LICONAJ (c) 2024

G4 P5000 ; WAIT 3 SECONDS
;MOVE ACTUATOR A
G1 A-60
G4 P500
G1 AO
G4 P500
;MOVE ACTUATOR B
G1 B-60
G4 P500
G1 BO
G4 P500
;MOVE ACTUATOR C
G1 C-60
G1 CO
;MOVE ACTUATORS A AND B
G4 P1000
G1 A-60 B-60
G4 P500
G1 AO BO
;MOVE ACTUATORS B AND C
G4 P1000
G1 B-60 C-60
G4 P500
G1 BO CO
;MOVE ACTUATORS C AND A
G4 P1000
G1 C-60 A-60
G4 P500
G1 CO AO
;MOVE ALL ACTUATORS
G4 P1000
G1 A-60 B-60 C-60
G4 P1000
;MOVE ACTUATORS A B C TO HOME
G28 A B C
```

D Command Line Interface Source Code

```
#!/usr/bin/python3
#alamctl.py

import serial
import sys
import argparse
import time
import serial.tools.list_ports

EOC = "!EOC"
EOL = "\r\n"

def get_ports():
    ports = []
    patterns = ["COM", "ttyACM", "ttyUSB"]
```

```

for pattern in patterns:
    ports += serial.tools.list_ports.grep(pattern)
return ports

def list_ports():
    ports = get_ports()
    for port in ports:
        print("{0:<20} \t {1:<30}".format(port.device, port.manufacturer))

parser = argparse.ArgumentParser()
parser.add_argument("-p", "--port", help="set device port")
parser.add_argument("-f", "--file", help="open G-CODE file")
parser.add_argument("-l", "--list", help="list available devices", action="store_true")
args = parser.parse_args()

if args.list:
    list_ports()
    sys.exit()

if args.port:
    port = args.port
else:
    ports = get_ports()
    print(f"{len(ports)} device(s) found")
    if not ports:
        print("No serial ports available")
        sys.exit()
    else:
        port = ports[0].device
        print(f"Connecting to {port}...")

try:
    mcu = serial.Serial(port=port, baudrate=250000, timeout=.1)
    time.sleep(1)
    response = mcu.readline().decode()
    if not response.startswith("this is alam"):
        print("Incompatible robot")
        sys.exit()
except serial.SerialException:
    print("Serial port unavailable")
    sys.exit()

def send_command(value: str):
    mcu.write(bytes(value, "utf-8"))

def parse_command(cmd: str) -> str:
    cmd = cmd.strip().split(";")[0]
    cmd += EOL
    # print(f"Parsing command {repr(cmd)}")
    send_command(cmd)
    output = ""
    value = ""
    while not EOC in value:
        value = mcu.readline().decode()
        if not EOC in value:
            output += value
    return output

if __name__ == "__main__":
    if args.file is None:
        print("\nAlam Control Center")
        print("By Josue Licona (C) 2024\n")

        print("G to show G-CODE commands")
        print("M to show M-CODE commands")
        print("Ctrl+C or ;EXIT to quit\n")

        try:
            while True:

```

```

        cmd = input("alam> ").upper()
        if ";EXIT" in cmd:
            break
        elif not cmd or cmd.startswith(";"):
            continue
        print(parse_command(cmd))
    except KeyboardInterrupt:
        print("\n\nPROGRAM ENDED BY USER\n")

else:
    time.sleep(1)
    try:
        with open(args.file, "r", encoding="utf-8") as fh:
            lines = fh.readlines()
            fh.close()
    except FileNotFoundError:
        print(f"File '{args.file}' not found")
        sys.exit()

    for cmd in lines:
        cmd = cmd.strip().upper()
        if not cmd or cmd.startswith(";"):
            continue
        print(f"> {cmd.strip()}")
        print(parse_command(cmd))

```

E Firmware Source Code

E.1 Arduino Main Entry Point

```

// AlamWare.ino

#include "Memory.h"
#include "Commands.h"

// SerialCommands Setup
char serialCommandBuffer[128];
SerialCommands serialCommands(&Serial, serialCommandBuffer, sizeof(serialCommandBuffer));

void addSerialCommands() {
    serialCommands.SetDefaultHandler(cmdUnrecognized);

    serialCommands.AddCommand(&GHelp);
    serialCommands.AddCommand(&G1);
    serialCommands.AddCommand(&G4);
    serialCommands.AddCommand(&G92);
    serialCommands.AddCommand(&G92_1);
    serialCommands.AddCommand(&G28);
    serialCommands.AddCommand(&G28_1);
    serialCommands.AddCommand(&G90);
    serialCommands.AddCommand(&G91);

    serialCommands.AddCommand(&MHelp);
    serialCommands.AddCommand(&M00);
    serialCommands.AddCommand(&M85);
    serialCommands.AddCommand(&M114);
    serialCommands.AddCommand(&M303);
    serialCommands.AddCommand(&M301);
    serialCommands.AddCommand(&M300);
}

void setup() {

```

```

    Serial.begin(250000);
    Serial.print("this is alam");
    addSerialCommands();
}

void loop() {
    if (testing) {
        updateTest();
    } else {
        serialCommands.ReadSerial();

        updateNamedActuators();
        nextCommand();
    }
}

```

E.2 Persistence Memory Management Class Header

```

// Memory.h

#ifndef MEMORY_H
#define MEMORY_H

#include <EEPROM.h>

class Memory {
private:
    float kp;
    float kd;
    float ki;

    uint8_t kpAddress = 10;
    uint8_t kiAddress = 12;
    uint8_t kdAddress = 14;

    int lastPositions[6];
    uint8_t pAddresses[6];

public:
    Memory();
    ~Memory();

    int GetLastPosition(uint8_t actuatorId);
    void SavePosition(uint8_t actuatorId, int position);
    void GetTunings(float* kp, float* ki, float* kd);
    void SaveTunings(float kp, float ki, float kd);
};

#endif

```

E.3 Persistence Memory Management Class

```

// Memory.cpp
#include "Memory.h"

Memory::Memory() {
    for (int i = 0; i < 6; i++) {
        pAddresses[i] = 20 + sizeof(float) * i;
    }
}

```

```

Memory::~Memory() {
}

void Memory::SavePosition(uint8_t actuatorId, int position) {
    EEPROM.put(pAddresses[actuatorId], position);
}

int Memory::GetLastPosition(uint8_t actuatorId) {
    return lastPositions[actuatorId];
}

void Memory::SaveTunings(float kp, float ki, float kd) {
    EEPROM.put(kpAddress, kp);
    EEPROM.put(kiAddress, ki);
    EEPROM.put(kdAddress, kd);
}

void Memory::GetTunings(float* kp, float* ki, float* kd) {
    EEPROM.get(kpAddress, kp);
    EEPROM.get(kiAddress, ki);
    EEPROM.get(kdAddress, kd);
}

```

E.4 Commands Definitions

```

// Commands.h
#ifndef COMMANDS_H
#define COMMANDS_H

#include "SerialCommands.h"
#include "NamedActuators.h"
#include "RodActuator.h"

bool sendingCommand = false;
bool testing = false;
unsigned long startTimeTest;

void updateTest();
void nextCommand();

// G-Code Definitions
void cmdUnrecognized(SerialCommands *, const char *);
void cmdGetGCodes(SerialCommands *);
void cmdDelay(SerialCommands *);
void cmdMoveActuator(SerialCommands *);
void cmdSetGlobalMode(SerialCommands *);
void cmdSetRelativeMode(SerialCommands *);
void cmdSetHome(SerialCommands *);
void cmdSetTarget(SerialCommands *);
void cmdMoveToHome(SerialCommands *);
void cmdMoveToTarget(SerialCommands *);

// M-Code Definitions
void cmdGetMCodes(SerialCommands *);
void cmdStop(SerialCommands *);
void cmdsetTimeout(SerialCommands *);
void cmdGetActuatorPositions(SerialCommands *);
void cmdTestActuators(SerialCommands *);
void cmdStartAutoTuning(SerialCommands *);
void cmdSetPIDConstants(SerialCommands *);

SerialCommand GHelp("G", &cmdGetGCodes);
SerialCommand G4("G4", &cmdDelay);
SerialCommand G1("G1", &cmdMoveActuator);
SerialCommand G28("G28", &cmdMoveToHome);
SerialCommand G28_1("G28.1", &cmdMoveToTarget);
SerialCommand G90("G90", &cmdSetGlobalMode);
SerialCommand G91("G91", &cmdSetRelativeMode);
SerialCommand G92("G92", &cmdSetHome);
SerialCommand G92_1("G92.1", &cmdSetTarget);

SerialCommand MHelp("M", &cmdGetMCodes);
SerialCommand M00("M00", &cmdStop);
SerialCommand M85("M85", &cmdSetTimeout);

```

```

SerialCommand M114("M114", &cmdGetActuatorPositions);
SerialCommand M300("M300", &cmdTestActuators);
SerialCommand M303("M303", &cmdStartAutoTuning);
SerialCommand M301("M301", &cmdSetPIDConstants);

void endCmd(SerialCommands *sender) {
    sender->GetSerial()->println("!EOC");
}

void nextCommand() {
    if (!sendingCommand)
        return;
    for (NamedActuator actuator : namedActuators) {
        if (!actuator.object->Next())
            return;
    }
    Serial.println("!EOC");
    sendingCommand = false;
}

float getvel(int t) {
    float v;
    float m = 255.0 / 500.0;
    if (t < 500 || t > 4000) {
        v = 0;
    } else if (t < 1000) { // entre 500 y 1000 ms rampa
        v = m * (t - 500);
    } else if (t < 1500) { // mantener velocidad máxima por 500 ms
        v = 255;
    } else if (t < 2000) { // disminuir velocidad
        v = -m * (t - 1500) + 255;
    } else if (t < 2500) { // mantener velocidad máxima en reversa por 500 ms
        v = 0;
    } else if (t < 3000) {
        v = -m * (t - 2500);
    } else if (t < 3500) {
        v = -255;
    } else if (t < 4000) {
        v = m * (t - 3500) - 255;
    }
    return v;
}

void updateTest() {
    unsigned long t = millis() - startTimeTest;
    Serial.print(t);
    float v = getvel(t);
    Serial.print(";");
    Serial.print(v);
    for (NamedActuator actuator : namedActuators) {
        Serial.print(";");
        actuator.object->TestVelocity(v);
        actuator.object->Update();
        Serial.print(actuator.object->GetPosition());
    }
    Serial.println("");
    if (t >= 4500) {
        testing = false;
        for (NamedActuator actuator : namedActuators) {
            actuator.object->Stop();
        }
        Serial.println("!EOC");
    }
}

void cmdUnrecognized(SerialCommands *sender, const char *cmd) {
    sendingCommand = true;
    sender->GetSerial()->print("Unrecognized command [");
    sender->GetSerial()->print(cmd);
    sender->GetSerial()->println("]");
}

void cmdGetGCodes(SerialCommands *sender) {
    sendingCommand = true;
    sender->GetSerial()->println("G: Show this help");
    sender->GetSerial()->println("G1: Move actuator");
    sender->GetSerial()->println("G4: Pause robot by a determined P<time>");
    sender->GetSerial()->println("G28: Move actuators to home position");
    sender->GetSerial()->println("G28.1: Move actuators to target position");
    sender->GetSerial()->println("G90: Set global positioning mode");
    sender->GetSerial()->println("G91: Set relative positioning mode");
    sender->GetSerial()->println("G92: Set home position");
    sender->GetSerial()->println("G92.1: Set target position");
}

void cmdGetMCodes(SerialCommands *sender) {
}

```

```

sendingCommand = true;
sender->GetSerial()->println("M: Show this help");
sender->GetSerial()->println("M00: Stop actuators");
sender->GetSerial()->println("M85: Set command timeout with P<milliseconds> or S<seconds>");
sender->GetSerial()->println("M114: Report actual position of actuators");
sender->GetSerial()->println("M300: Test actuators");
sender->GetSerial()->println("M301: Set PID constants with P<value> I<value> D<value>");
sender->GetSerial()->println("M303: Starts autotuning");
}

void cmdDelay(SerialCommands *sender) {
    sendingCommand = true;

    // sender->GetSerial()->println("Starting delay");
    char *arg = sender->Next();
    if (arg != NULL) {
        char parameter = arg[0];
        float value = atof(arg + 1);
        if (parameter == 'P') {
            delay(value);
        }
    }
}

void cmdMoveActuator(SerialCommands *sender) {
    sendingCommand = true;
    uint8_t speed = 255;
    char *arg;
    while ((arg = sender->Next()) != NULL) {
        char id = arg[0];
        float value = atof(arg + 1);
        if (id == 'F') {
            speed = value;
            continue;
        }
        RodActuator *actuator = getActuatorByName(id);
        actuator->Move(value);
        actuator->SetMaxSpeed(speed);
    }
}

void cmdStop(SerialCommands *sender) {
    sendingCommand = true;
    for (NamedActuator actuator : namedActuators) {
        actuator.object->Stop();
    }
}

void cmdSetTimeout(SerialCommands *sender) {
    sendingCommand = true;
    float maximumTimeout = 60e3;
    float timeout = 5000;
    char *arg = sender->Next();
    if (arg != NULL) {
        char parameter = arg[0];
        float value = atof(arg + 1);
        if (parameter == 'P') {
            timeout = value;
        } else if (parameter == 'S') {
            timeout = value * 1000;
        }
        if (timeout > maximumTimeout)
            timeout = maximumTimeout;
        for (NamedActuator actuator : namedActuators) {
            actuator.object->SetTimeout(timeout);
        }
    } else {
        timeout = namedActuators[0].object->GetTimeout();
    }
    sender->GetSerial()->print("Timeout:");
    sender->GetSerial()->println(timeout);
}

void cmdGetActuatorPositions(SerialCommands *sender) {
    sendingCommand = true;

    int decimalPlaces = 5;

    String positions = "";
    for (int i = 0; i < N_ACTUATORS; ++i) {
        String name = (String)namedActuators[i].name;
        float position = namedActuators[i].object->GetPosition();
        positions += name + ":" + String(position);
        if (i < N_ACTUATORS - 1) {
            {
                positions += " ";
            }
        }
    }
}

```

```

        }
        sender->GetSerial()->println(positions);
    }

void cmdStartAutoTuning(SerialCommands *sender) {
    sendingCommand = true;

    char *arg;
    while ((arg = sender->Next()) != NULL) {
        char id = arg[0];
        Serial.print("Starting auto tuning in actuator ");
        Serial.println(id);
        RodActuator *actuator = getActuatorByName(id);
        actuator->AutoTune();
    }
}

void cmdTestActuators(SerialCommands *sender) {
    testing = true;
    startTimeTest = millis();
    sender->GetSerial()->print("t");
    sender->GetSerial()->print(",PWM");
    for (NamedActuator actuator : namedActuators) {
        sender->GetSerial()->print(";");
        sender->GetSerial()->print(actuator.name);
    }
    sender->GetSerial()->println("");
}

void cmdSetPIDConstants(SerialCommands *sender) {
    sendingCommand = true;

    float kp = 0;
    float ki = 0;
    float kd = 0;

    char *arg;
    while ((arg = sender->Next()) != NULL) {
        char id = arg[0];
        float value = atof(arg + 1);
        if (id == 'P')
            kp = value;
        else if (id == 'I')
            ki = value;
        else if (id == 'D')
            kd = value;
    }

    for (NamedActuator actuator : namedActuators) {
        actuator.object->SetPIDConstants(kp, ki, kd);
    }

    sender->GetSerial()->print("Kp:");
    sender->GetSerial()->print(kp);
    sender->GetSerial()->print(" Kd:");
    sender->GetSerial()->print(kd);
    sender->GetSerial()->print(" Ki:");
    sender->GetSerial()->println(ki);
}

void cmdSetGlobalMode(SerialCommands *sender) {
    for (NamedActuator actuator : namedActuators) {
        actuator.object->SetMoveMode(actuator.object->Global);
    }
}

void cmdSetRelativeMode(SerialCommands *sender) {
    for (NamedActuator actuator : namedActuators) {
        actuator.object->SetMoveMode(actuator.object->Relative);
    }
}

void cmdSetHome(SerialCommands *sender) {
    sendingCommand = true;
    char *arg;
    while ((arg = sender->Next()) != NULL) {
        char id = arg[0];
        float value = atof(arg + 1);
        RodActuator *actuator = getActuatorByName(id);
        actuator->SetHomePosition(value);
    }
}

void cmdSetTarget(SerialCommands *sender) {
    sendingCommand = true;
    char *arg;
    while ((arg = sender->Next()) != NULL) {
        char id = arg[0];
        float value = atof(arg + 1);
    }
}

```

```

    RodActuator *actuator = getActuatorByName(id);
    actuator->SetTargetPosition(value);
}

void cmdMoveToHome(SerialCommands *sender) {
    sendingCommand = true;
    char *arg;
    arg = sender->Next();
    if (arg == NULL) {
        for (NamedActuator actuator : namedActuators) {
            actuator.object->MoveToHome();
        }
    } else {
        char id = arg[0];
        float value = atof(arg + 1);
        RodActuator *actuator = getActuatorByName(id);
        actuator->MoveToHome();

        while ((arg = sender->Next()) != NULL) {
            id = arg[0];
            float value = atof(arg + 1);
            actuator = getActuatorByName(id);
            actuator->MoveToHome();
        }
    }
}

void cmdMoveToTarget(SerialCommands *sender) {
    sendingCommand = true;
    char *arg;
    arg = sender->Next();
    if (arg == NULL) {
        for (NamedActuator actuator : namedActuators) {
            actuator.object->MoveToTarget();
        }
    } else {
        char id = arg[0];
        float value = atof(arg + 1);
        RodActuator *actuator = getActuatorByName(id);
        actuator->MoveToTarget();

        while ((arg = sender->Next()) != NULL) {
            id = arg[0];
            float value = atof(arg + 1);
            actuator = getActuatorByName(id);
            actuator->MoveToTarget();
        }
    }
}

#endif

```

E.5 Actuators Instances

```

// NamedActuators.h
#ifndef NAMEDACTUATORS_H
#define NAMEDACTUATORS_H

#include "RodActuator.h"

// 1.1
#define A_ENA 21
#define A_ENB 24
#define A_IN1 13
#define A_IN2 12
// 1.3
#define B_ENA 20
#define B_ENB 23
#define B_IN1 6
#define B_IN2 7
// 2.2
#define C_ENA 3
#define C_ENB 66
#define C_IN1 10
#define C_IN2 11
// 2.1
#define I_ENA 19
#define I_ENB 65
#define I_IN1 9
#define I_IN2 8
// 2.3
#define J_ENA 2
#define J_ENB 64
#define J_IN1 5
#define J_IN2 4

```

```

// 1.2
#define K_ENA 18
#define K_ENB 22
#define K_IN1 44
#define K_IN2 45

enum Actuators {
    A, B, C, I, J, K,
    N_ACTUATORS
};

struct NamedActuator {
    char name;
    RodActuator *object;
};

// Posiciones
volatile long angPosition[N_ACTUATORS] = {0, 0, 0, 0, 0, 0};

// Interrupt Handlers
// static void A_interruptHandler() {
//     if (digitalRead(A_ENA) != digitalRead(A_ENB))
//         angPosition[A]++;
//     else
//         angPosition[A]--;
// }
static void B_interruptHandler() {
    if (digitalRead(B_ENA) != digitalRead(B_ENB))
        angPosition[B]++;
    else
        angPosition[B]--;
}
static void C_interruptHandler() {
    if (digitalRead(C_ENA) != digitalRead(C_ENB))
        angPosition[C]++;
    else
        angPosition[C]--;
}
static void I_interruptHandler() {
    if (digitalRead(I_ENA) != digitalRead(I_ENB))
        angPosition[I]++;
    else
        angPosition[I]--;
}
static void J_interruptHandler() {
    if (digitalRead(J_ENA) != digitalRead(J_ENB))
        angPosition[J]++;
    else
        angPosition[J]--;
}
static void K_interruptHandler() {
    if (digitalRead(K_ENA) != digitalRead(K_ENB))
        angPosition[K]++;
    else
        angPosition[K]--;
}

NamedActuator namedActuators[N_ACTUATORS] = {
    {'A', new RodActuator(A_ENA, A_ENB, A_IN1, A_IN2, angPosition[A], A_interruptHandler)},
    {'B', new RodActuator(B_ENA, B_ENB, B_IN1, B_IN2, angPosition[B], B_interruptHandler)},
    {'C', new RodActuator(C_ENA, C_ENB, C_IN1, C_IN2, angPosition[C], C_interruptHandler)},
    {'I', new RodActuator(I_ENA, I_ENB, I_IN1, I_IN2, angPosition[I], I_interruptHandler)},
    {'J', new RodActuator(J_ENA, J_ENB, J_IN1, J_IN2, angPosition[J], J_interruptHandler)},
    {'K', new RodActuator(K_ENA, K_ENB, K_IN1, K_IN2, angPosition[K], K_interruptHandler)},
};

RodActuator *getActuatorByName(char name) {
    for (int i = 0; i < N_ACTUATORS; ++i) {
        if (namedActuators[i].name == name)
            return namedActuators[i].object;
    }
    return nullptr;
}

void updateNamedActuators() {
    for (NamedActuator actuator : namedActuators) {
        actuator.object->Update();
    }
}

#endif

```

E.6 Actuator Class Header

```
//RodActuator.h
#ifndef RODACTUATOR_H
#define RODACTUATOR_H

#include <Arduino.h>
#include <QuickPID.h>
#include <sTune.h>

class RodActuator {
public:
    RodActuator(uint8_t ENA, uint8_t ENB, uint8_t IN1, uint8_t IN2,
                volatile long &angPosition, void (*interruptHandler)());
    enum MoveMode {
        Global,
        Relative
    };
    void Stop();
    void Update();
    void SetPIDConstants(float Kp, float Ki, float Kd);
    void Move(float desiredPosition);
    float GetPosition();
    int GetTimeout();
    void TestVelocity(float velocity);
    void SetLeftLimit(float leftLimit);
    void SetRightLimit(float rightLimit);
    void SetMaxSpeed(uint8_t maxSpeed);
    void SetMoveMode(MoveMode);
    void SetTimeout(float timeout);
    void MoveToHome();
    void MoveToTarget();
    void SetHomePosition(float newHomePosition);
    void SetTargetPosition(float newSecondHomePosition);
    float GetHomePosition();
    float GetTargetPosition();
    void AutoTune();
    bool Next();

private:
    float homePosition = 0;
    float targetPosition = 0;

    bool isStable(float threshold);
    volatile long &angPosition;
    uint8_t IN1; // Pin forward velocity
    uint8_t IN2; // Pin backwards velocity
    uint8_t ENA; // Pin encoder A
    uint8_t ENB; // Pin encoder B

    float ticksRev = 7.0; // ticks in angPosition that makes a rev
    float gearRatio = 210.0; // reduction gear of gearRatio:1
    float R = 5.3;
    float positionFactor;

    uint8_t speed = 255;
    unsigned long timeout = 5000;
    unsigned long timer = millis();
    float position = 0;
    float lastPosition = 0;
    float desiredPosition = 0;
    float lastAngvelocity = 0;
    float angVelocity = 0; // motor angular position

    MoveMode moveMode = Global;

    bool next = true;
    bool move = false;
    float Kp, Kd, Ki;
    float outputMin = -255;
    float outputMax = 255;
    float outputSpan;
    bool startup = false;
    QuickPID PID; // Controlador PID

    bool test = false;
    bool tune = false;
    sTune tuner = sTune(&position, &angVelocity, tuner.NoOvershoot_PI, tuner.directIP, tuner.printALL);

    float _leftLimit = -2000;
    float _rightLimit = 2000;

    void updateVelocity();
    void updatePosition();
};

#endif
```

E.7 Actuator Class

```

//RodActuator.cpp
#include "RodActuator.h"
#include <Arduino.h>
#define DEBUG false

RodActuator::RodActuator(uint8_t ENA, uint8_t ENB, uint8_t IN1, uint8_t IN2,
    volatile long &angPosition, void (*interruptHandler)()):
    ENA(ENA), ENB(ENB), IN1(IN1), IN2(IN2), angPosition(angPosition) {
    pinMode(ENA, INPUT);
    pinMode(ENB, INPUT);
    pinMode(IN1, OUTPUT);
    pinMode(IN2, OUTPUT);

    attachInterrupt(digitalPinToInterruption(ENA), interruptHandler, CHANGE);

    // Calculate position factor
    // 1 Revolución en el encoder son 7 cambios
    // La relación de engranajes de 235:1
    // El valor de _position está en revoluciones
    // 1/(7*235) = 6.0790273556231e-4
    positionFactor = 2.0 * R * PI / (ticksRev * gearRatio);

    // Inicializar control PID
    PID = QuickPID(&position, &angVelocity, &desiredPosition);
    PID.SetOutputLimits(outputMin, outputMax);
    PID.SetSampleTimeUs(2030);
    PID.SetDerivativeMode(QuickPID::dMode::dOnError);
    PID.SetProportionalMode(QuickPID::pMode::pOnError);
    PID.SetAntiWindupMode(QuickPID::iAwMode::iAwCondition);
    PID.SetMode(QuickPID::Control::automatic);
    PID.SetTunings(22.1, 67, 3.8632);
}

void RodActuator::Update() {
    updatePosition();

    if (tune) {
        switch (tuner.Run()) {
            case tuner.sample:
                updateVelocity();
                break;

            case tuner.tunings:
                angVelocity = 0;
                updateVelocity();
                tuner.GetAutoTunings(&Kp, &Ki, &Kd);
                SetPIDConstants(Kp, Ki, Kd);
                tune = false;
                next = true;
                break;

            default:
                break;
        }
    }

    else if (move) {
        if (startup && position > desiredPosition - 10) {
            startup = false;
            angVelocity = 0.01 * angVelocity;
            updateVelocity();
            PID.SetMode(QuickPID::Control::manual);
            PID.SetMode(QuickPID::Control::automatic);
        }
        PID.Compute();
        updateVelocity();
    }

    else if (test) {
        updateVelocity();
    }

    lastPosition = position;
    lastAngVelocity = angVelocity;

    if (isStable(1.5)) {
        next = true;
    }

    if (!next && move) {
        unsigned long currentTime = millis();
        if (currentTime - timer > timeout) {
            next = true;
        }
    }
}

```

```

}

void RodActuator::Stop() {
    angVelocity = 0;
    next = true;
    move = false;
    test = false;
    updateVelocity();
    updatePosition();
}

void RodActuator::Move(float desiredPosition) {
    next = false;
    timer = millis();
    move = true;
    startup = true;
    if (moveMode == MoveMode::Global) {
        RodActuator::desiredPosition = desiredPosition;
    } else if (moveMode == MoveMode::Relative) {
        RodActuator::desiredPosition += desiredPosition;
    }
}

float RodActuator::GetHomePosition() {
    return homePosition;
}

float RodActuator::GetTargetPosition() {
    return targetPosition;
}

void RodActuator::SetHomePosition(float newHome) {
    RodActuator::homePosition = newHome;
}

void RodActuator::SetTargetPosition(float newSecondHome) {
    RodActuator::targetPosition = newSecondHome;
}

void RodActuator::MoveToHome() {
    float desiredPosition = homePosition;
    if (moveMode == MoveMode::Relative) {
        desiredPosition = homePosition - desiredPosition;
    }
    Move(desiredPosition);
}

void RodActuator::MoveToTarget() {
    float desiredPosition = targetPosition;
    if (moveMode == MoveMode::Relative) {
        desiredPosition = targetPosition - desiredPosition;
    }
    Move(desiredPosition);
}

float RodActuator::GetPosition() {
    return position;
}

void RodActuator::SetPIDConstants(float Kp, float Ki, float Kd) {
    Kp = Kp;
    Ki = Ki;
    Kd = Kd;
    PID.SetTunings(Kp, Ki, Kd);
}

bool RodActuator::Next() {
    return next;
}

void RodActuator::SetMaxSpeed(uint8_t maxSpeed) {
    if (maxSpeed < 50) {
        maxSpeed = 50;
    }
    RodActuator::speed = maxSpeed;
}

void RodActuator::TestVelocity(float velocity) {
    RodActuator::angVelocity = velocity;
    test = true;
}

void RodActuator::SetTimeout(float timeout) {
    RodActuator::timeout = timeout;
}

int RodActuator::GetTimeout() {
    return timeout;
}

void RodActuator::AutoTune() {
    tune = true;
    next = false;
}

```

```

    tuner.Configure(1000, 200, 100, 0, 3, 1, 500);
    tuner.SetEmergencyStop(1000);
}

void RodActuator::SetMoveMode(MoveMode moveMode) {
    RodActuator::moveMode = moveMode;
}

// =====
// Private methods
// =====
bool RodActuator::isStable(float threshold = 1) {
    return abs(position - desiredPosition) <= threshold;
}

void RodActuator::updateVelocity() {
    uint8_t vel1 = 0;
    uint8_t vel2 = 0;
    float minInput = 0;
    uint8_t minPWM = 0;
    if (angVelocity > minInput) {
        // vel1 = abs((float)_angVelocity / (float)_outputMax) * (float)_speed;
        vel1 = map(abs(angVelocity), minInput, outputMax, minPWM, RodActuator::speed);
        if (vel1 < 40)
            vel1 = 0;
    } else if (angVelocity < -minInput) {
        // vel2 = abs((float)_angVelocity / (float)_outputMax) * (float)_speed;
        vel2 = map(abs(angVelocity), minInput, outputMax, minPWM, RodActuator::speed);
        if (vel2 < 40)
            vel2 = 0;
    }
    // Serial.println(vel1);
    if (DEBUG && (move && !next)) {
        Serial.print("Velocity: ");
        Serial.print(angVelocity);
        Serial.print(" ");
        Serial.print(vel1);
        Serial.print(" ");
        Serial.print(vel2);
        Serial.print(" Position: ");
        Serial.print(position);
        Serial.println();
    }
    analogWrite(IN1, vel1);
    analogWrite(IN2, vel2);
}

void RodActuator::updatePosition() {
    position = angPosition * positionFactor;
}

```
