APSC 496

Technical Analysis Report

Praxim - Surgical Robot

(Draft Version 1)

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# Abstract

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# Introduction

# Structural

# Gravity Compensation

# Motors

After winnowing down the motor types we can use to DC and stepper, we needed to perform a technical analysis on quantitative requirements for the hard-constraint system. In order to choose the correct motor, a power rating had to be specified. This power rating depends on the torque the motor must be able to provide and the speed the motor must be able to operate at.

## Torque

According to last year’s group, the torque the motor needed to supply was 7.5 Nm: “After researching various motor and motor controller combinations, the Maxon EC-Max 25W Brushless DC motor (Figure 47) matched with a 66:1 gearbox was selected. It was selected because it provided sufficient nominal torque, acceleration, and maximum velocity for the experimentally derived expected moment of 7.5 Nm (50 N force at 15cm) discussed in Section 3.” We preformed our own analysis on the newer linkage design and came up with a substantially smaller value of around 1 Nm. This result if most likely due to the fact that the newer linkage design reduces the amount of force needed to be applied at the hard constraint, due to the action of friction on the vertical rod and the partial load-carrying of the rod and linkages. The analysis was preformed with the following linkage design:

L2

Load

Θ1

Θ2

Load

L1

A spreadsheet was made to compute the value of the hard-constraint force that is need at Link 1 (L1) with varying θs. Knowing the moment arm o the motor at that point, we can figure out the motor torque required. This spreadsheet proved to be very useful, as we could easily change the link lengths, the load, and the motor arm and immediately get the corresponding data. With link lengths of L1 = 15 cm and L2 = 10 cm, a load of 15 kg (hand force and the weight of the system), and a motor moment arm of 1 cm, we got back the following torque-theta curve:

\****θ1 (deg) is does not go below 48 degrees due to the different link lengths***

With the same load and moment values, but equal link length of 10 cm, the following curve is obtained (with a max torque of 1.5 Nm):

**Speed:**

# Control System

## Choosing a Control System

In choosing a processing unit for the control system, the criteria most concerning the device are speed, programming difficulty and cost. The table below highlights the options available in a general sense.

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
|  | Programming  Difficulty | Speed | Power | Cost | Display |
| 8/ 16 bit microcontroller | Moderate | Fast  ~20MHz | Low  <1W | ~$50 | Difficult to add |
| 32 bit microcontroller | Moderate | Very fast  ~600MHz | Low  1-5W | ~$150-400 | Possible |
| 32 bit x86 microcontroller (PC) | Easy/moderate | Slow/fast  (depending on OS) | High  <50W | ~$150-500 | Easy to add |

How fast of a microcontroller do we need? We know that the system as a whole must update at a rate of at minimum 1kHz.



## Determining the PID Gains

## Determining the Accuracy

# Conclusion

# Appendix