

# Contents

|   |  |   |
|---|--|---|
| 1 | Name of Candidate and Provisional Thesis Title | 1 |
| 2 | Keywords                                       | 1 |
| 3 | Research Field and Motivation                  | 1 |
| 4 | State of the Art                               | 2 |
| 5 | Work Accomplished                              | 3 |

## 1 Name of Candidate and Provisional Thesis Title

**Candidate Name:** Sean THOMAS

**Provisional Thesis Title:** Smart Grippers: Conception of a novel type of actuator powered by Shape Memory Alloys

## 2 Keywords

Shape Memory Alloy, Buckled Beam, NiTiNOL, Shape Memory Effect, Bistable system, Self-switching, Modeling and Optimization, Printed Electronics

## 3 Research Field and Motivation

### 3.1 Motivation

In an era where manual assembly is no longer possible in the majority of developed countries, it is necessary for companies offering alternative solutions to stand out from their competitors. Manufacturers of assembly lines must modify the capabilities of their robots in order to be as competitive as possible compared to the relocation of the assembly in countries with cheaper labour. In order to stand out, companies such as Mikron SA, seek to increase the efficiency of their installations while preserving the precision appreciated by their customers. The goal of this project would be to conceive and develop a novel and innovative type of Smart gripper. This small part plays a primordial role in the dynamics of the robot. Being at the end of the arm, a small gain in weight of this part would have great consequences on the acceleration and the maximum speed that the robot will be able to reach.

The *Laboratory of Integrated Actuators*, along with a Swiss company, *Mikron SA*, intend to develop a novel type of gripper that will harness the high work output per volume of Shape Memory Alloys (SMA). This gripper would be designed to be lightweight and compact so as to be used as a pick and place gripper in clean room application. The project strives to create an innovative technology that will exploit the characteristics of this smart material to create an actuator that is highly responsive, dynamic, lightweight and compact. These objective will motivate a doctoral thesis that is challenging and innovative.

### 3.2 Research Field

This project will focus on high response SMA actuation with a large stroke. The greatest challenge to overcome and the reason why this very promising technology is often left out

of industrial application is due to its large response time which is in the order of a second. Heating the element is not the greatest challenge, the cooling time of the material must also be taken into account. It is important to note that it is often harder to dissipate heat rather than accumulate it. Thus, various heating and cooling solutions will be exploited and investigated during this project.

This investigation will consider the thermal and mechanical aspect of the material so as to create a highly responsive and dynamic actuator capable of achieving the required force output of traditional grippers. The main focus of the research will be the thermal and mechanical optimization. The conception of the gripper will include optimization of the geometrical topology of the SMA blades and the use of bistable systems such as buckled beams to create dynamic and high stroke actuators. The command strategies of the actuator will also be an important area of study due to the fact that the actuation of the SMA will involve the precise control of its temperature and resistance.

The symbiosis of the bistable system and the SMA technology can result in an innovative gripper system. The interplay between these two domains will be studied and explored in this thesis.

### 3.3 Specifications

## 4 State of the Art

This section will discuss the existing smart materials that are currently studied and used in the domain of actuators. The different techniques and integration systems will also be presented with the goal to compare the various approaches currently used.

### 4.1 Smart materials

In the field of engineering, ranging from haptics, automation and bio-medical fields, there has been a need to create actuators that are lightweight, compact and having force output. This creates a need for materials that can deliver high forces and strokes while remaining light and small meaning that the materials need to have a high work output.

On the basis of creating an actuator that can meet the demands of the currently implemented strategies while at the same time pushing the limits of the current technology, a thorough investigation of the available smart materials must be conducted. These materials have the ability to react to an external stimulus such as thermal electrical or magnetic and are thus referred to as *smart* or *active materials*. These materials have an inherent property that allows them to be exploited with a specific external stimulus so as to alter their mechanical characteristics or to create self-sensing technology.

There exist numerous types of smart materials and based on their properties, they can be classified into many types such as :

- Piezoelectric materials
- Magneto-strictive materials
- Electro-active polymers
- Shape Memory Alloys

## **5 Work Accomplished**

### **References**