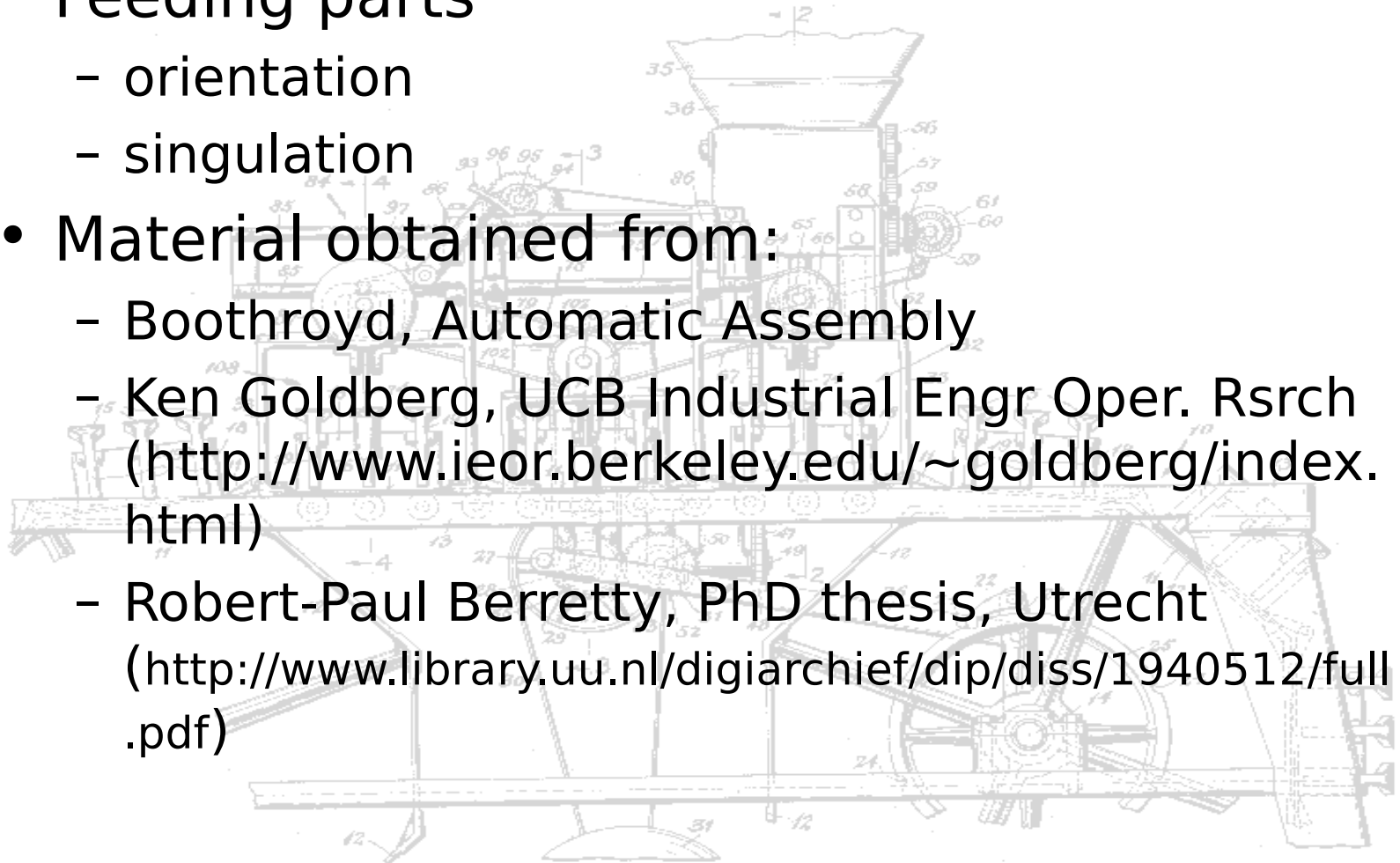


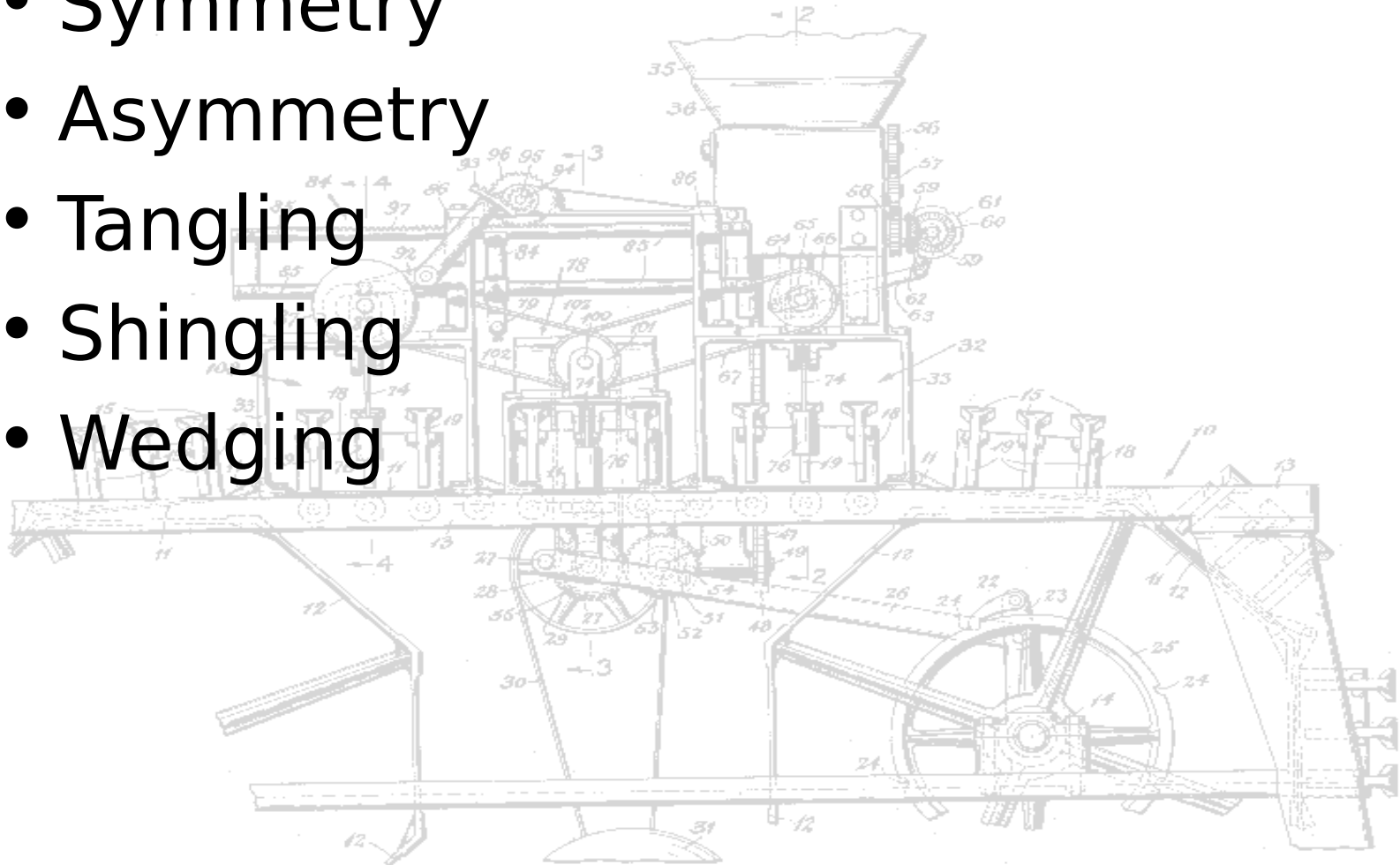
Care & Feeding of Machines

- Feeding parts
 - orientation
 - singulation
- Material obtained from:
 - Boothroyd, Automatic Assembly
 - Ken Goldberg, UCB Industrial Engr Oper. Rsrch (<http://www.ieor.berkeley.edu/~goldberg/index.html>)
 - Robert-Paul Berretty, PhD thesis, Utrecht (<http://www.library.uu.nl/digiarchief/dip/diss/1940512/full.pdf>)

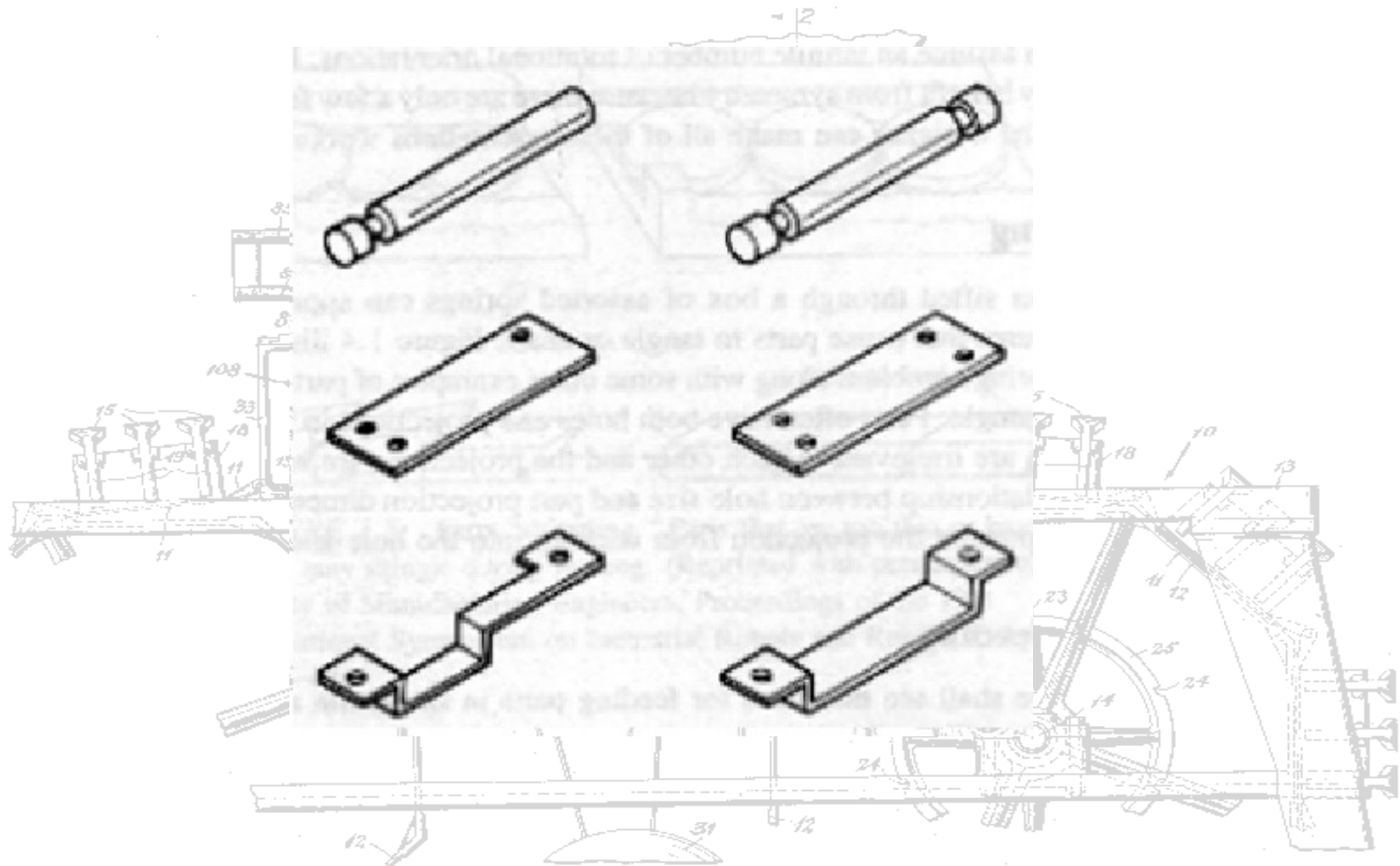


Designing Parts for Feeding

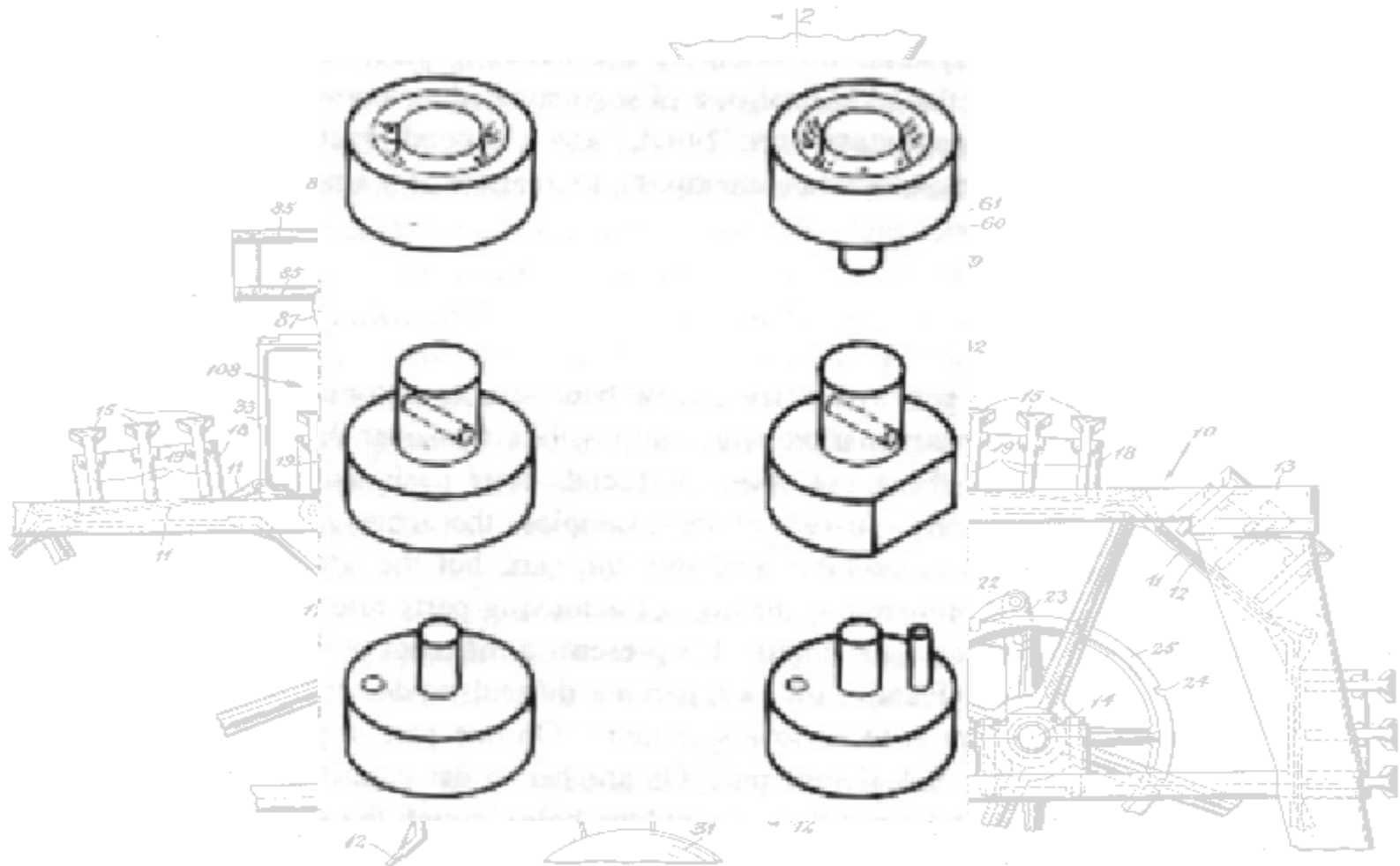
- Symmetry
- Asymmetry
- Tangling
- Shingling
- Wedging



Symmetry



Asymmetry

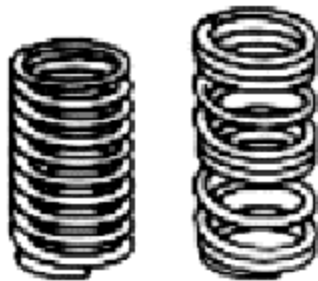


Tangling

Difficult to feed



Preferred



Opening less than wire diameter prevents nesting

Difficult to feed



Preferred



Open ends



Closed ends



Tight coils prevent nesting

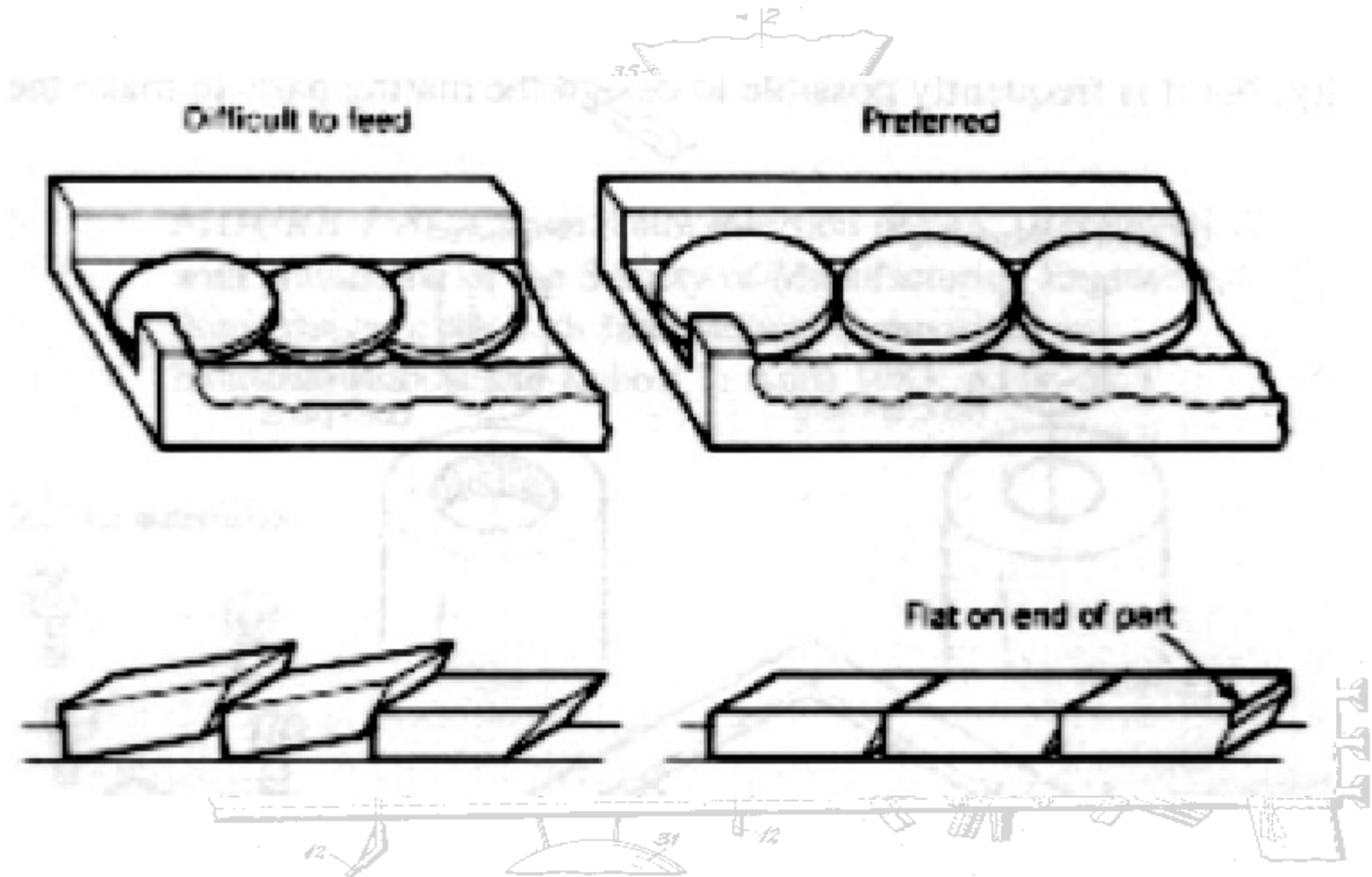
Larger tab



Smaller hole

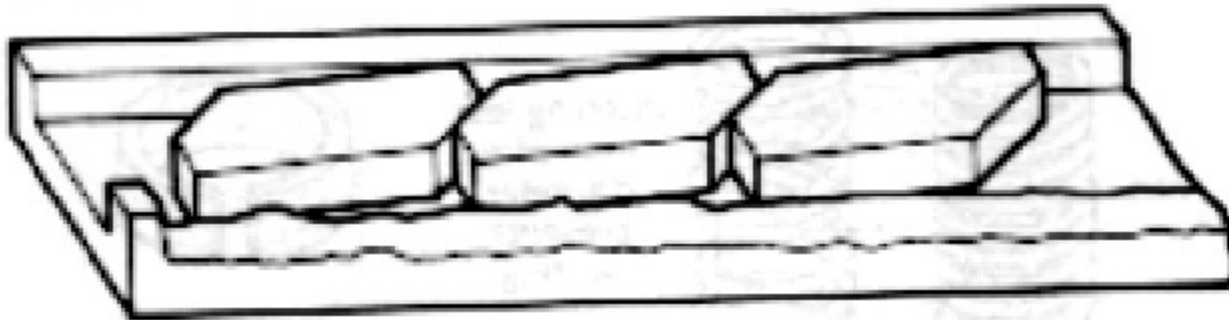


Shingling

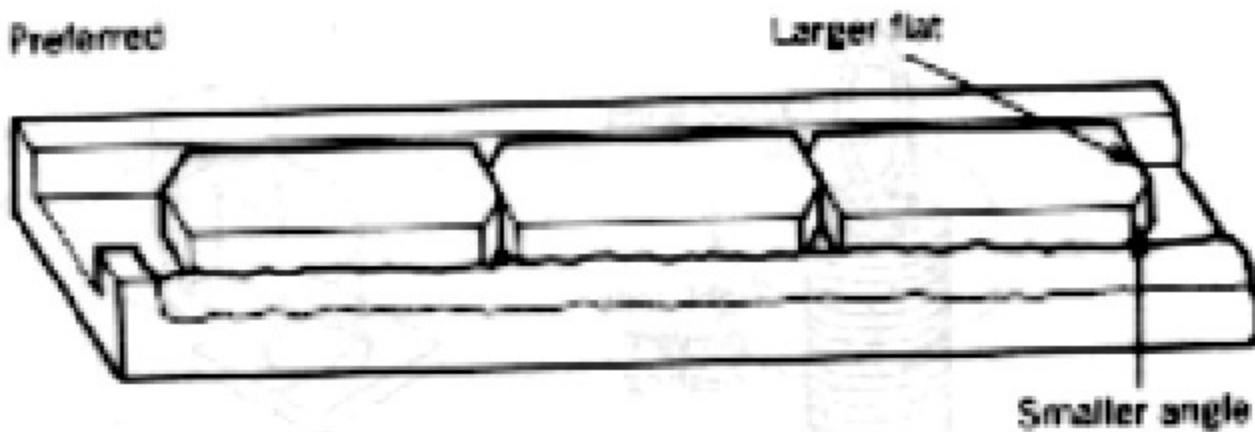


Wedging

Difficult to feed

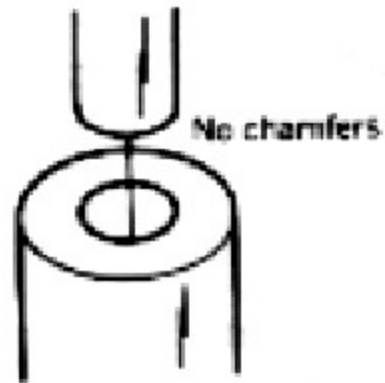


Preferred

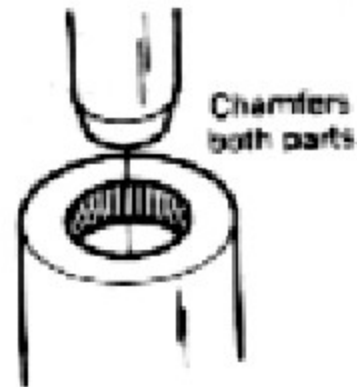


Designing for Insertion

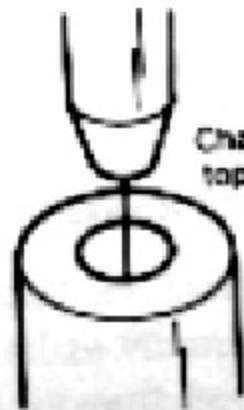
Difficult to assemble



Preferred



Chamfer top part



Chamfer bottom part

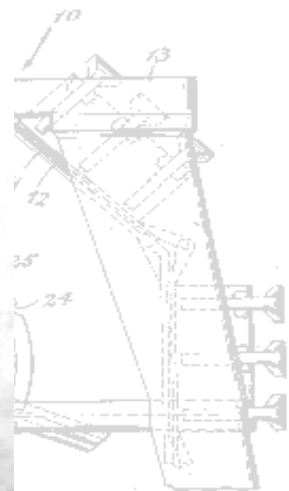
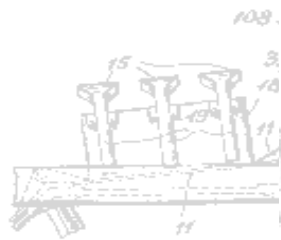


Diagram illustrating the conditions for wedging during the assembly of a peg into a hole.

Key parameters and labels:

- d : Diameter of Peg
- L : Distance from hole axis to start of chamfer
- l : Distance from hole axis to end of chamfer
- μ : Coefficient of friction
- D : Hole diameter

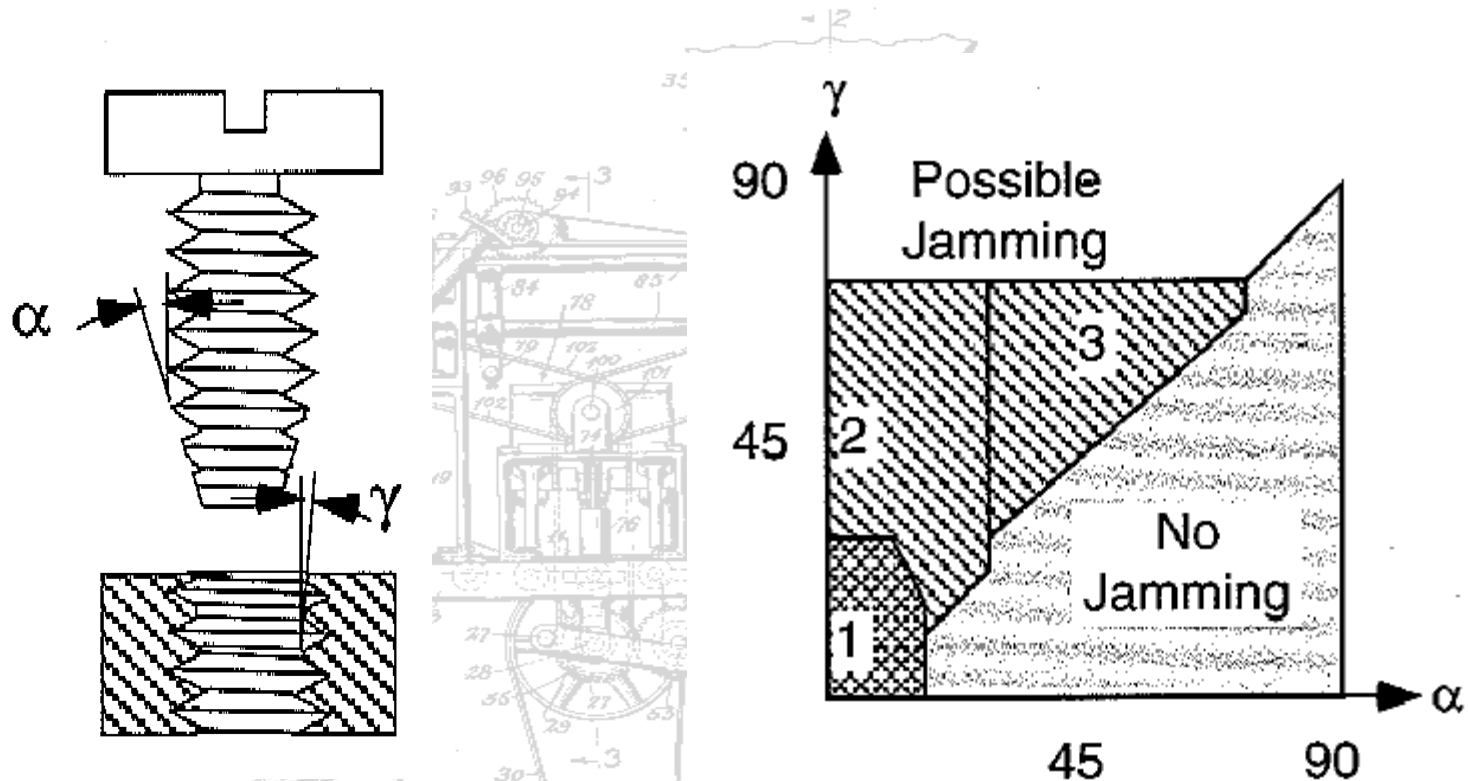
Assembly stages and contact states:

- Approach**: Initial approach of the peg.
- First Contact on Chamfer**: Initial contact occurs on the chamfer.
- One-point Contact**: Initial contact is a single point.
- Two-point Contact: Jamming Possible**: Contact transitions to two points, where jamming is possible.
- First Contact on Bore**: Contact transitions to the bore.
- Done**: Final state after assembly.

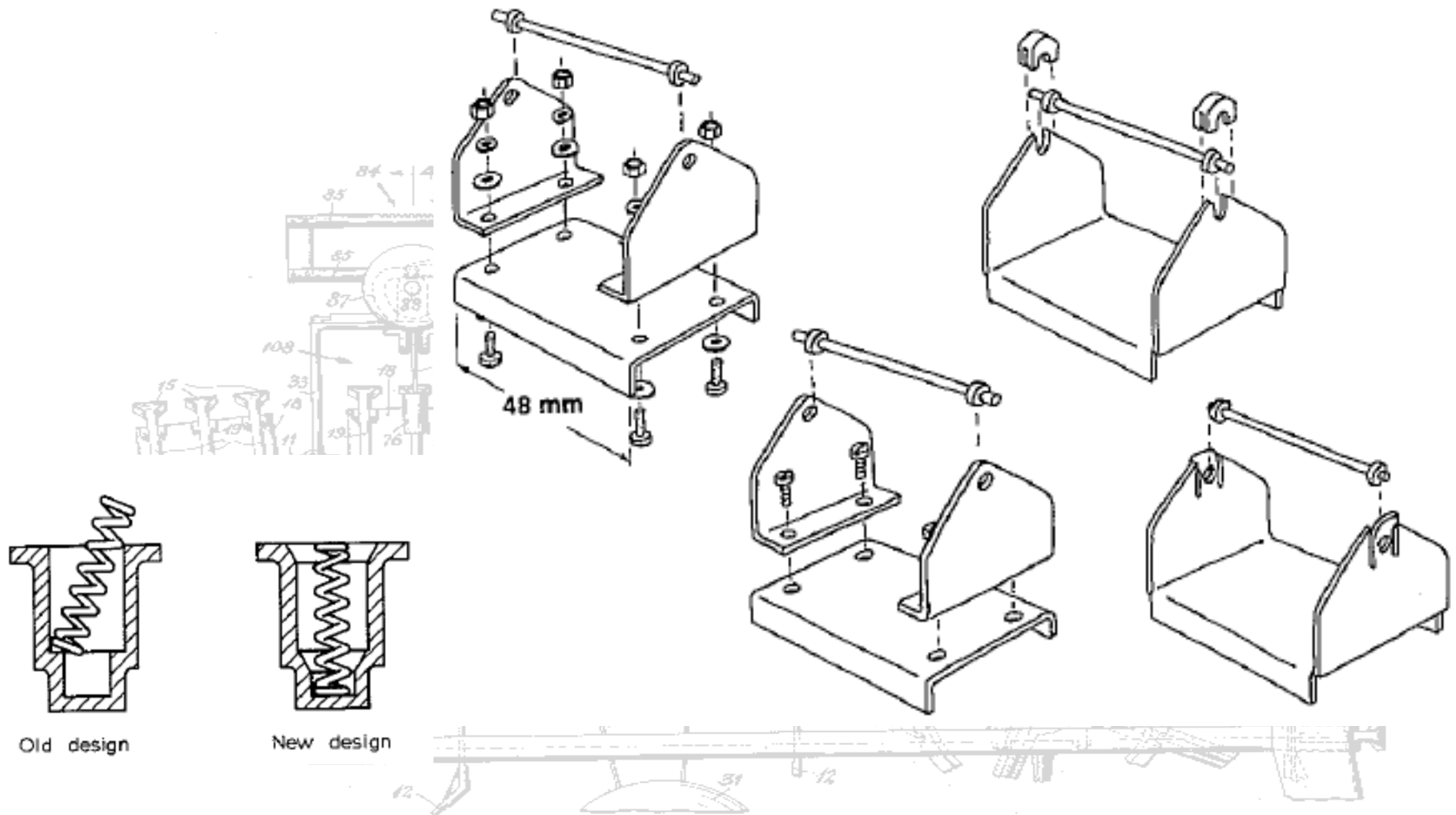
Wedge conditions:

- If $l < \mu D$, **Wedge Possible During Two-point Contact**.
- If $l > \mu D$, **Wedge Impossible**.

Screw Thread Mating

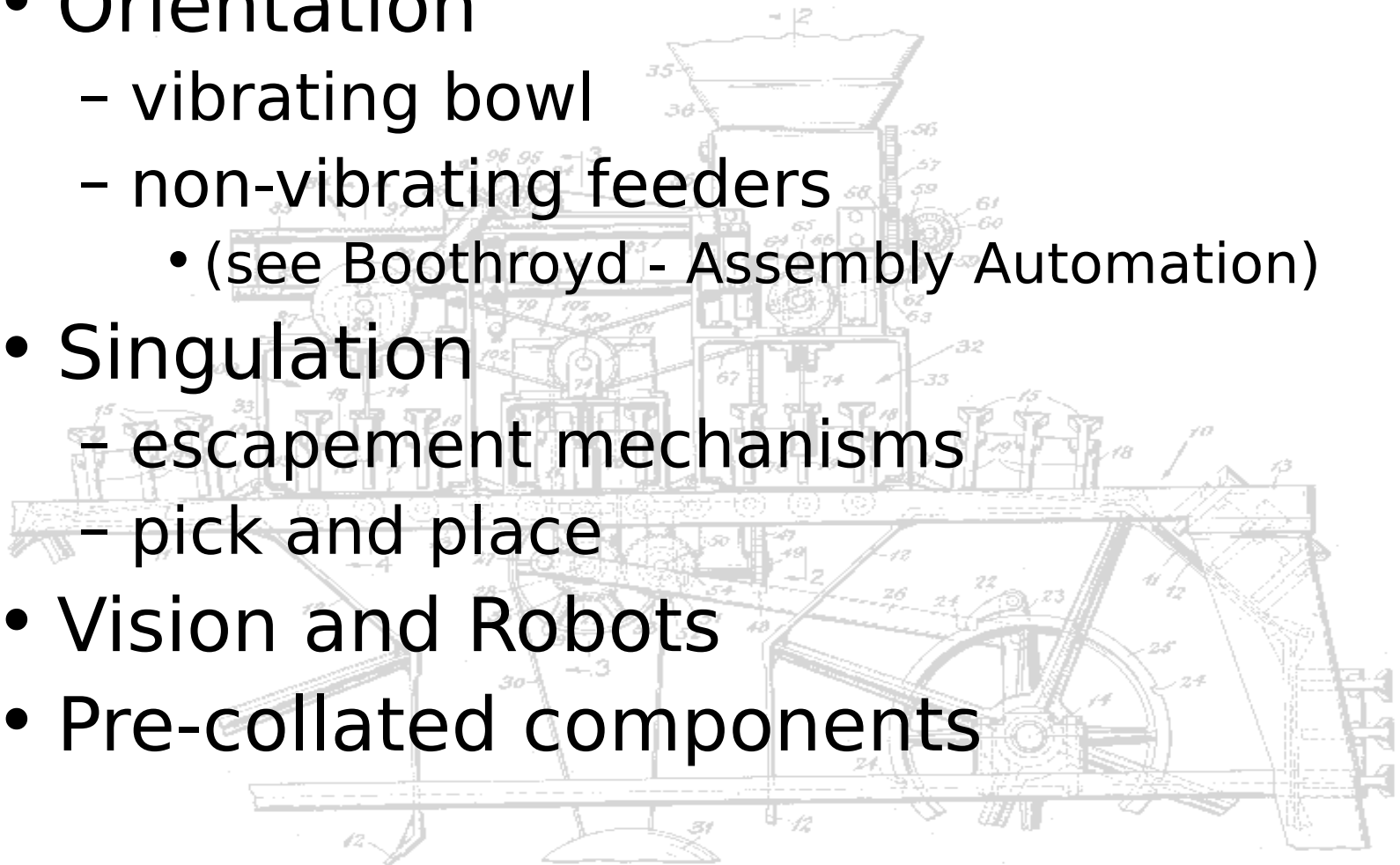


Simplifying the Design



Fastener Feeding Requirements

- Orientation
 - vibrating bowl
 - non-vibrating feeders
 - (see Boothroyd - Assembly Automation)
- Singulation
 - escapement mechanisms
 - pick and place
- Vision and Robots
- Pre-collated components



Singulation

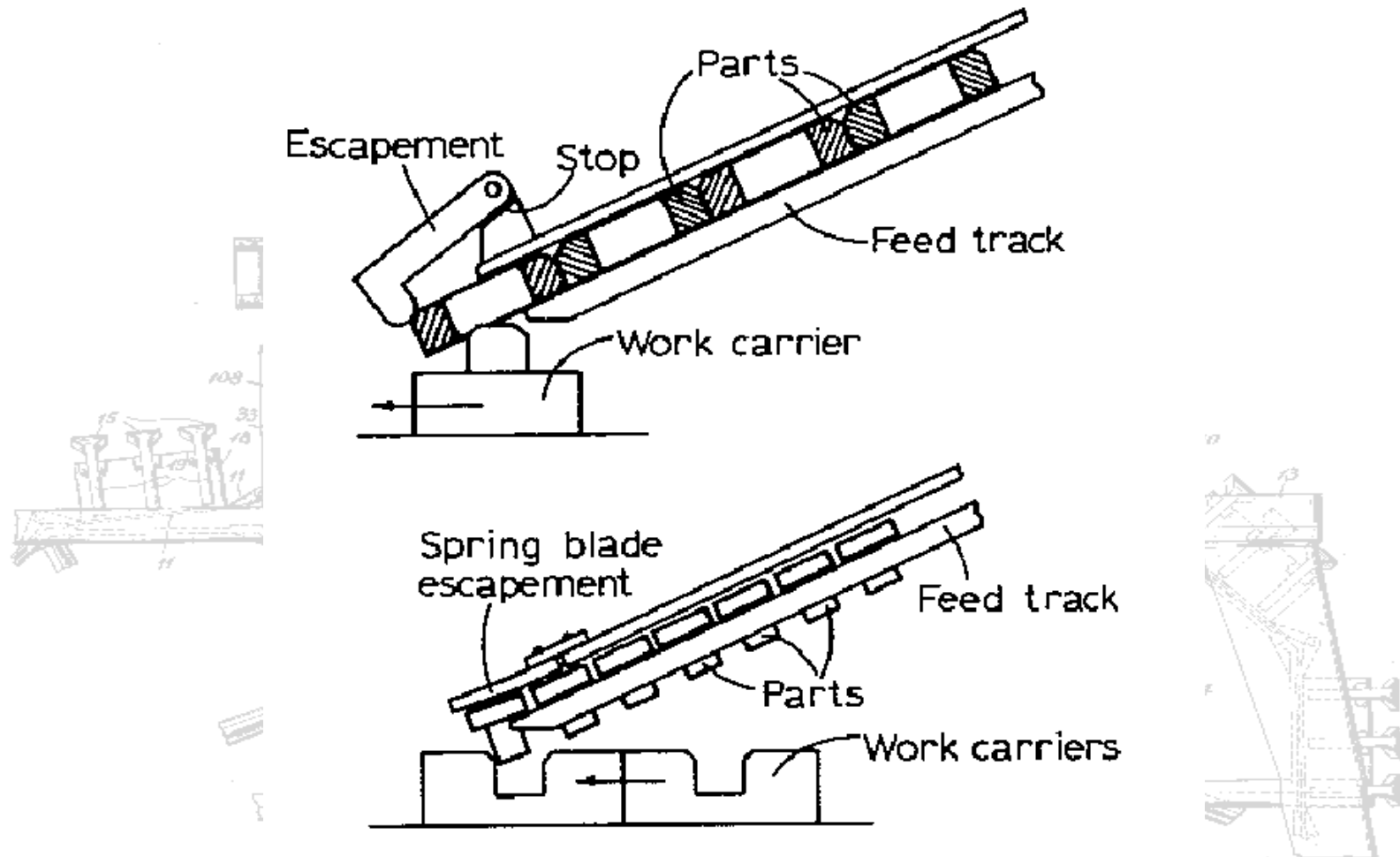


Fig. 5.24 Escapements actuated by the work carrier.

Singulation

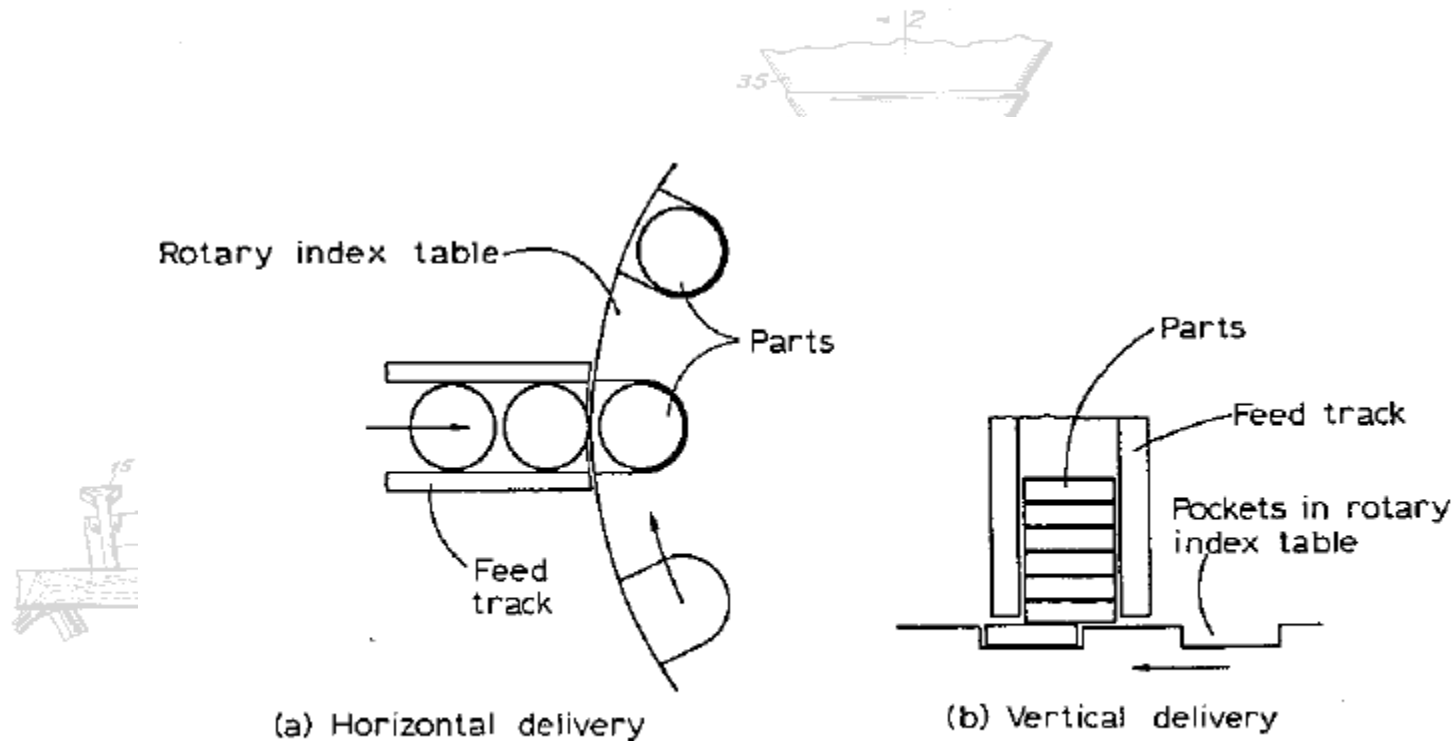
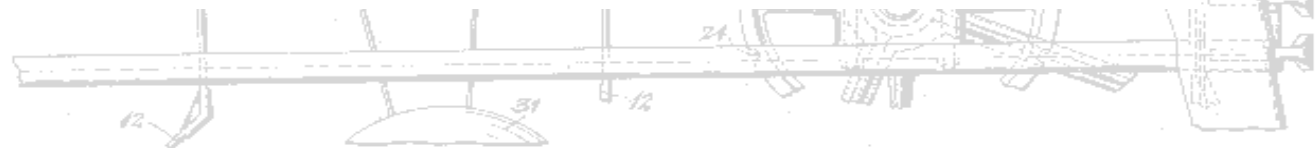
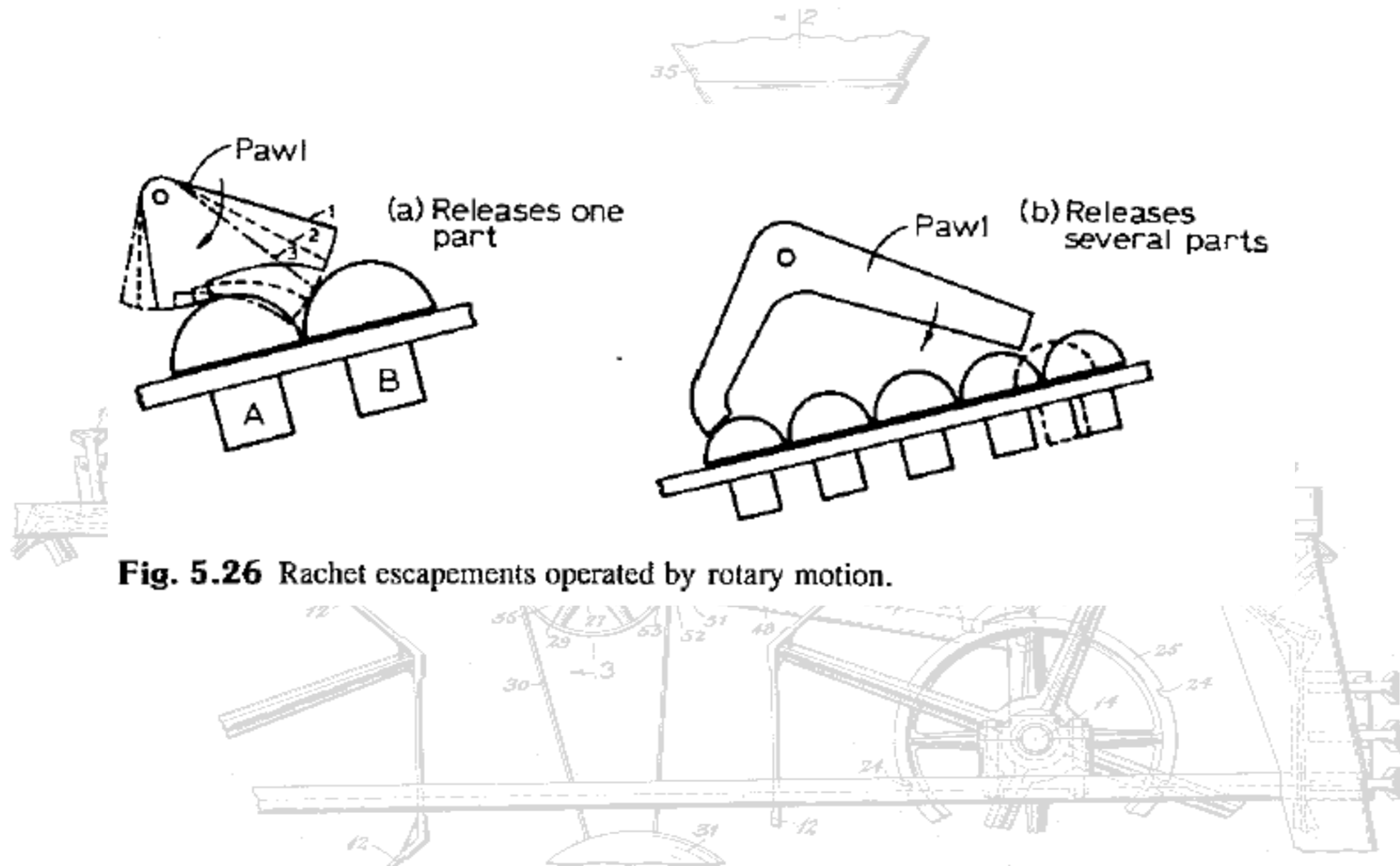


Fig. 5.25 Feeding of parts onto rotary index table.



Singulation



Singulation

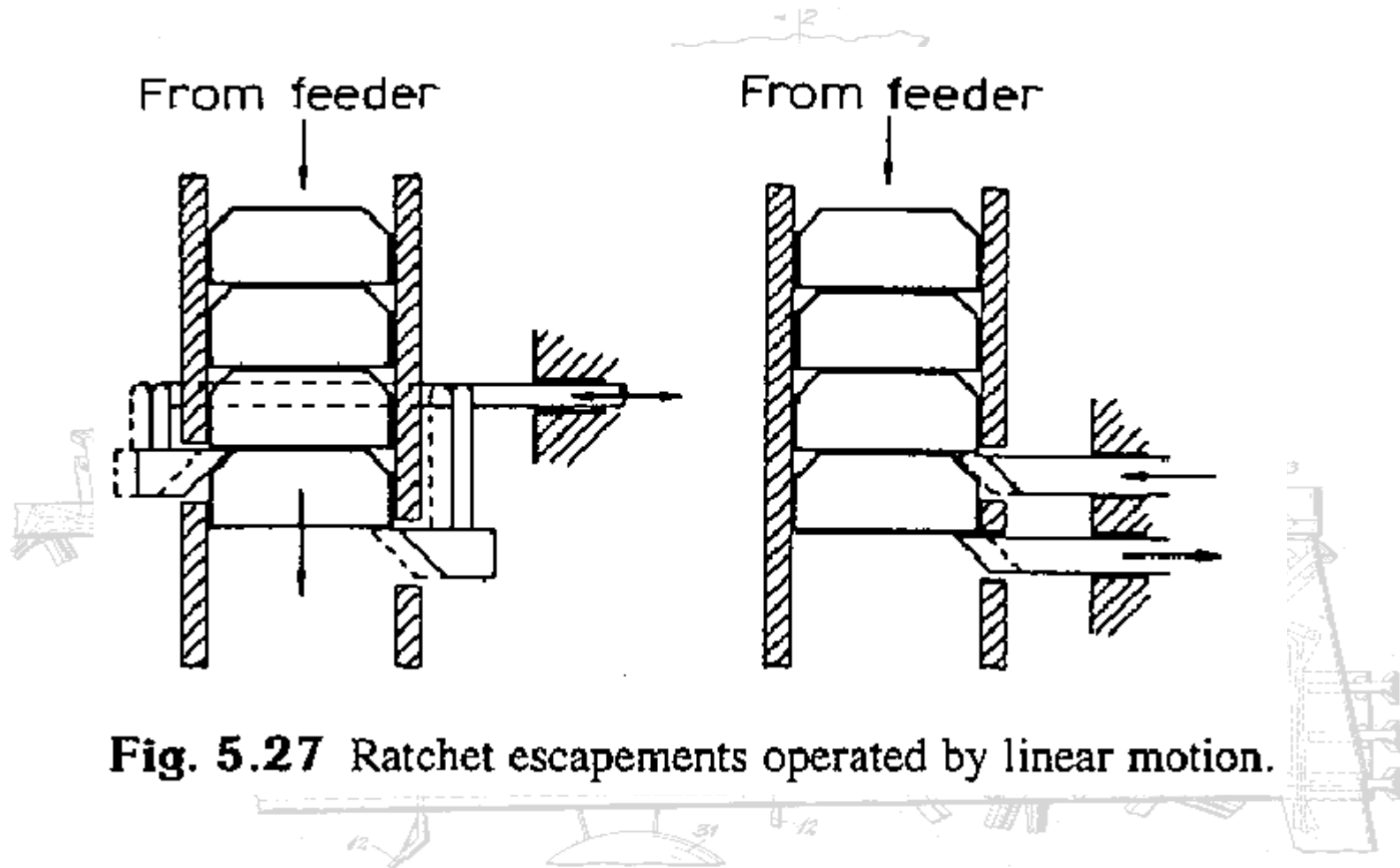
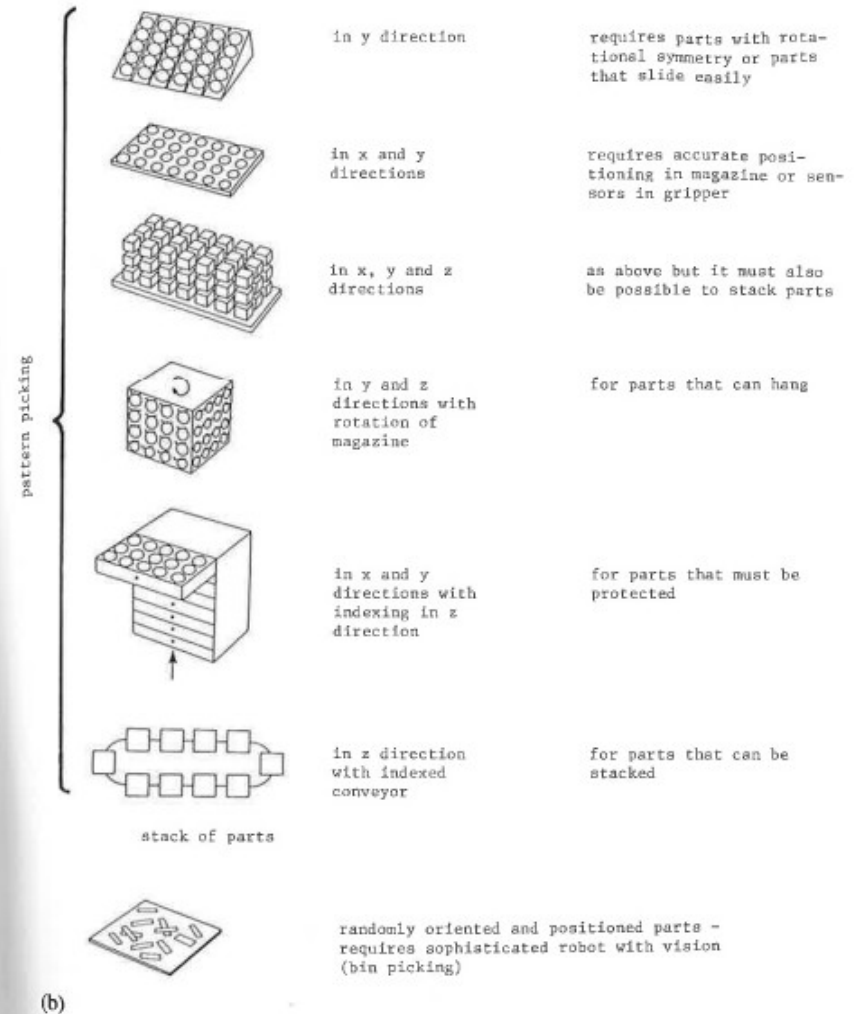
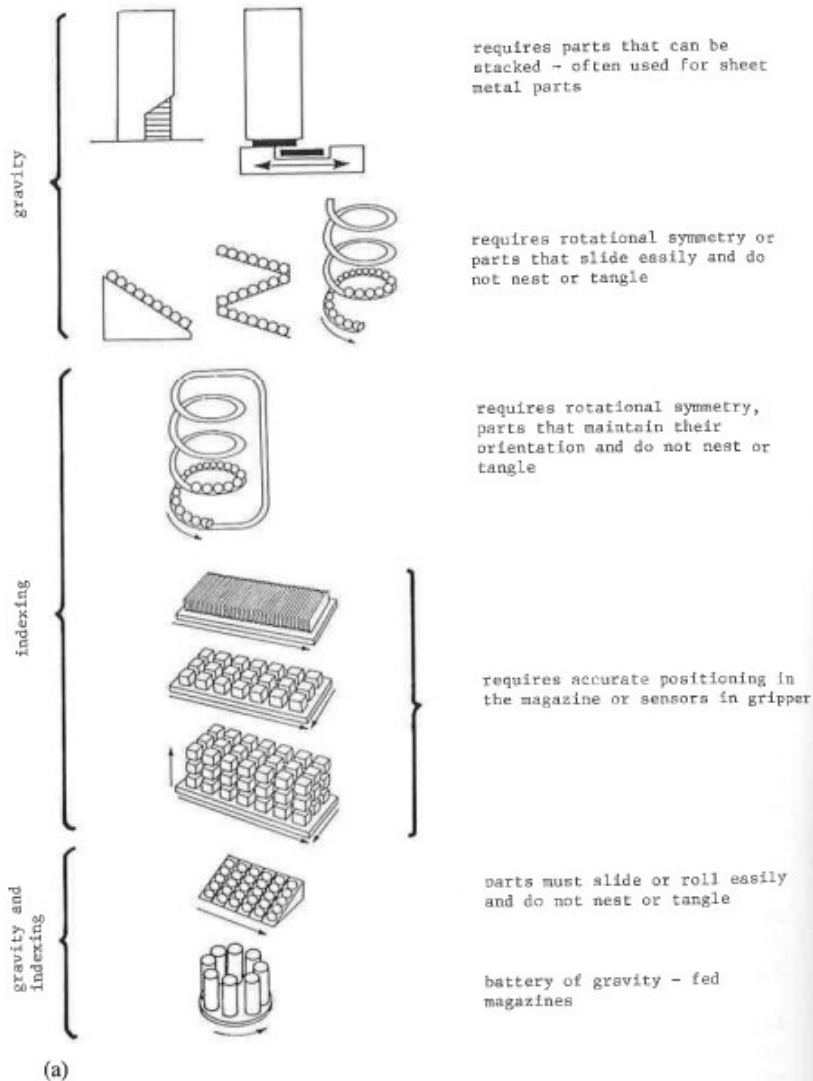


Fig. 5.27 Ratchet escapements operated by linear motion.

Variety of Feeding Methods



(a) Cylinder part

(b) Flat parts

(c) Screws

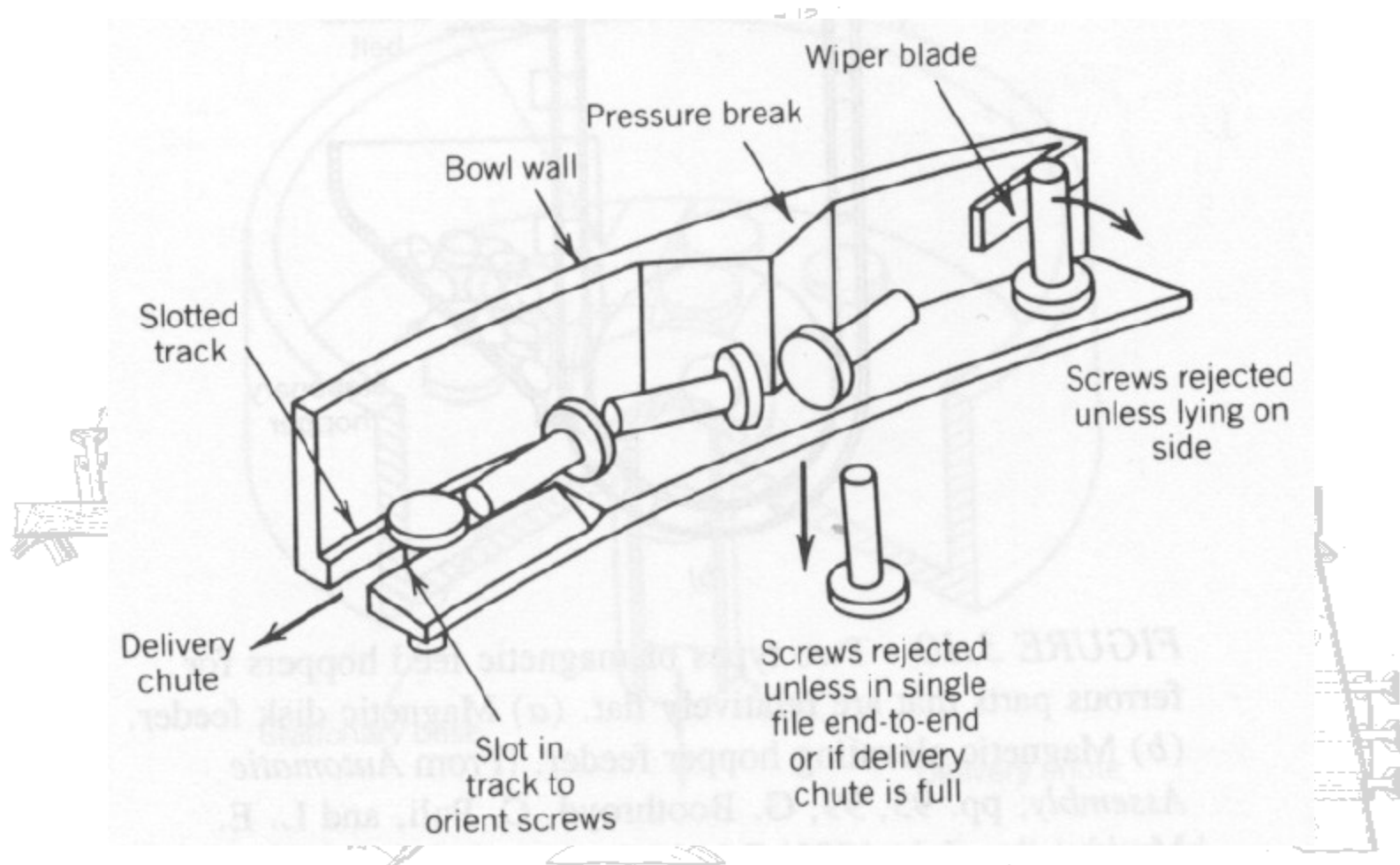
Bowl Feeders



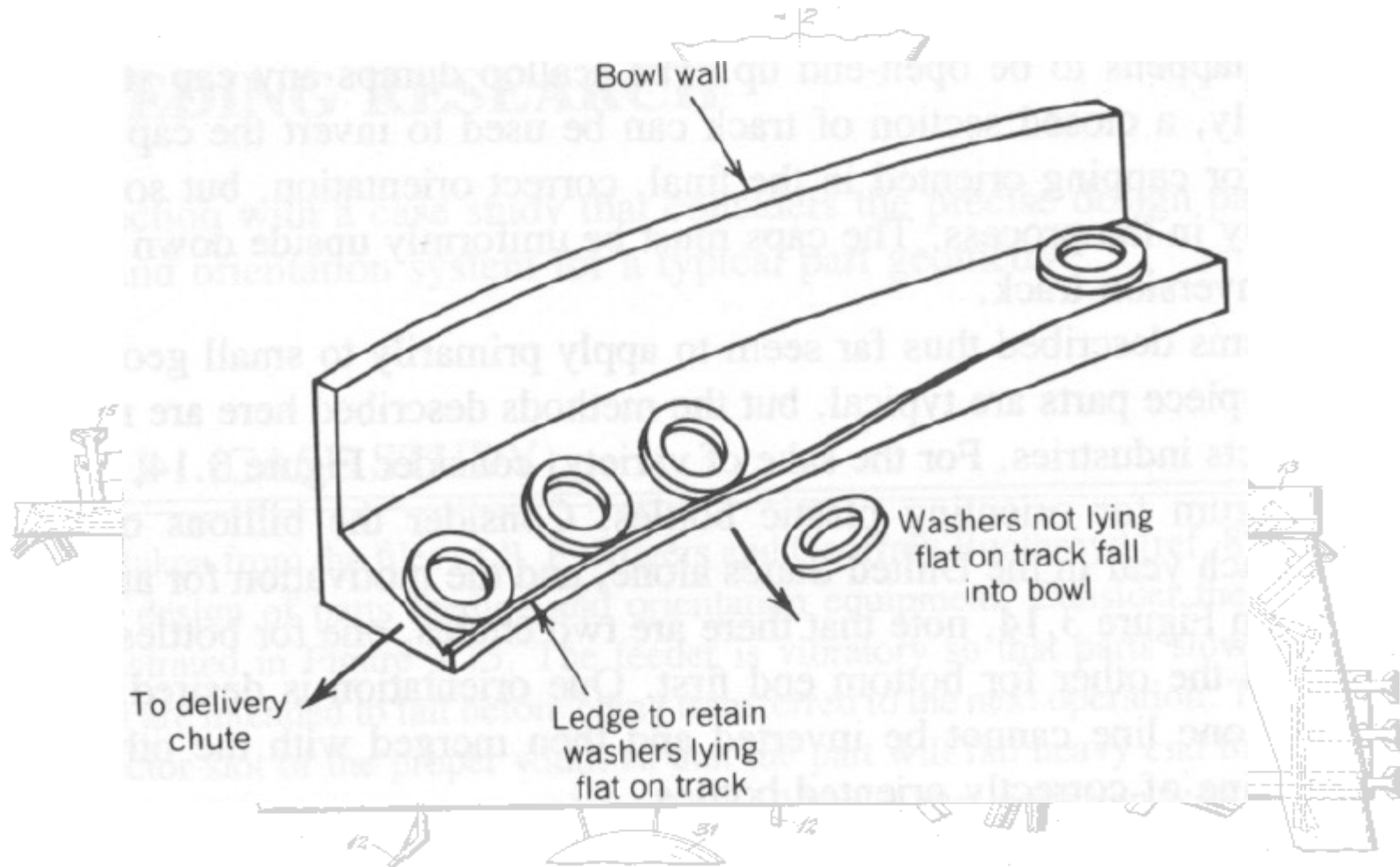
Bowl Feeders



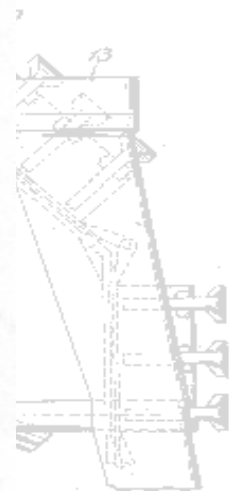
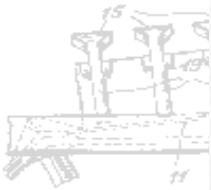
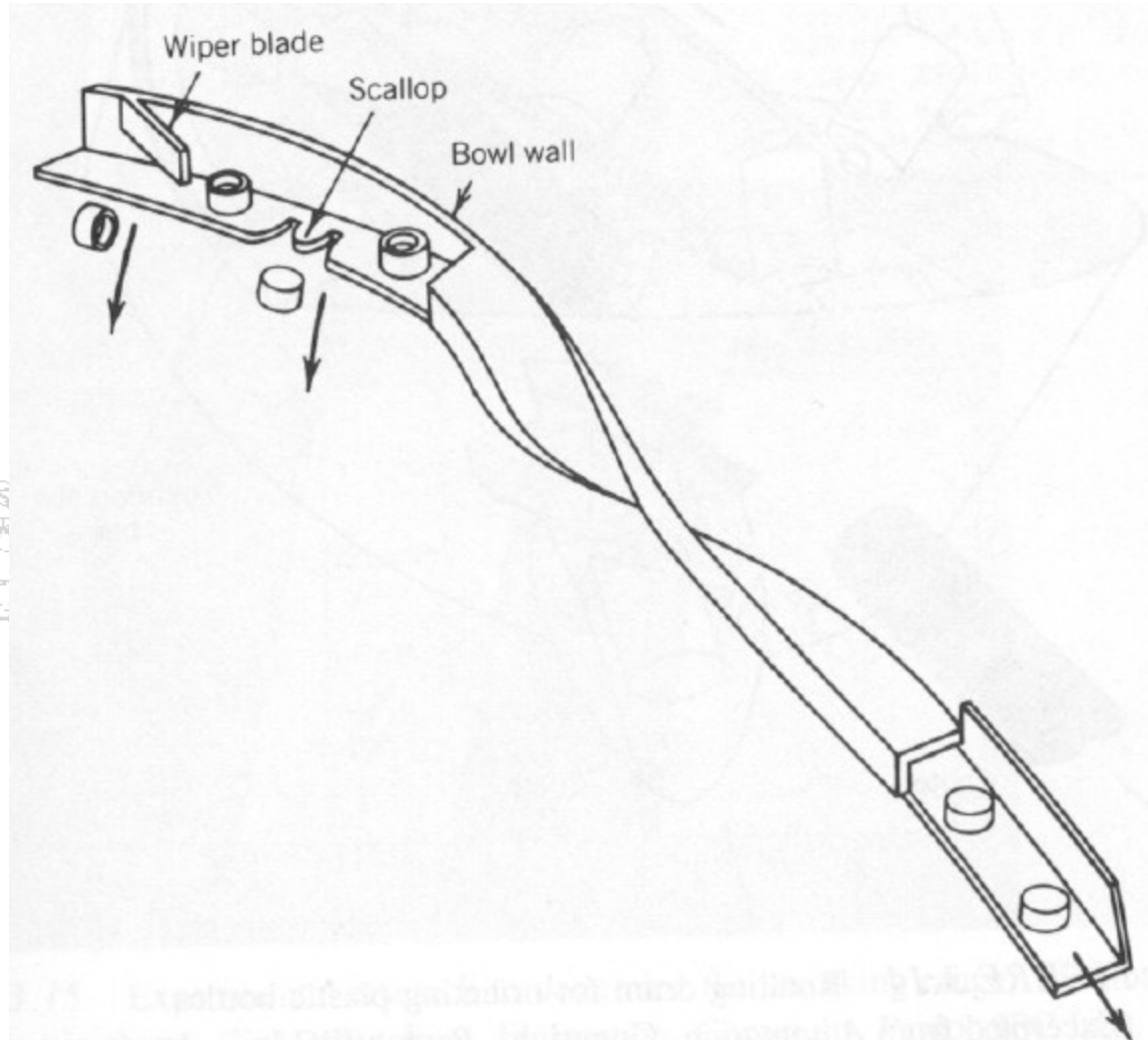
Bowl Feeders



Bowl Feeders

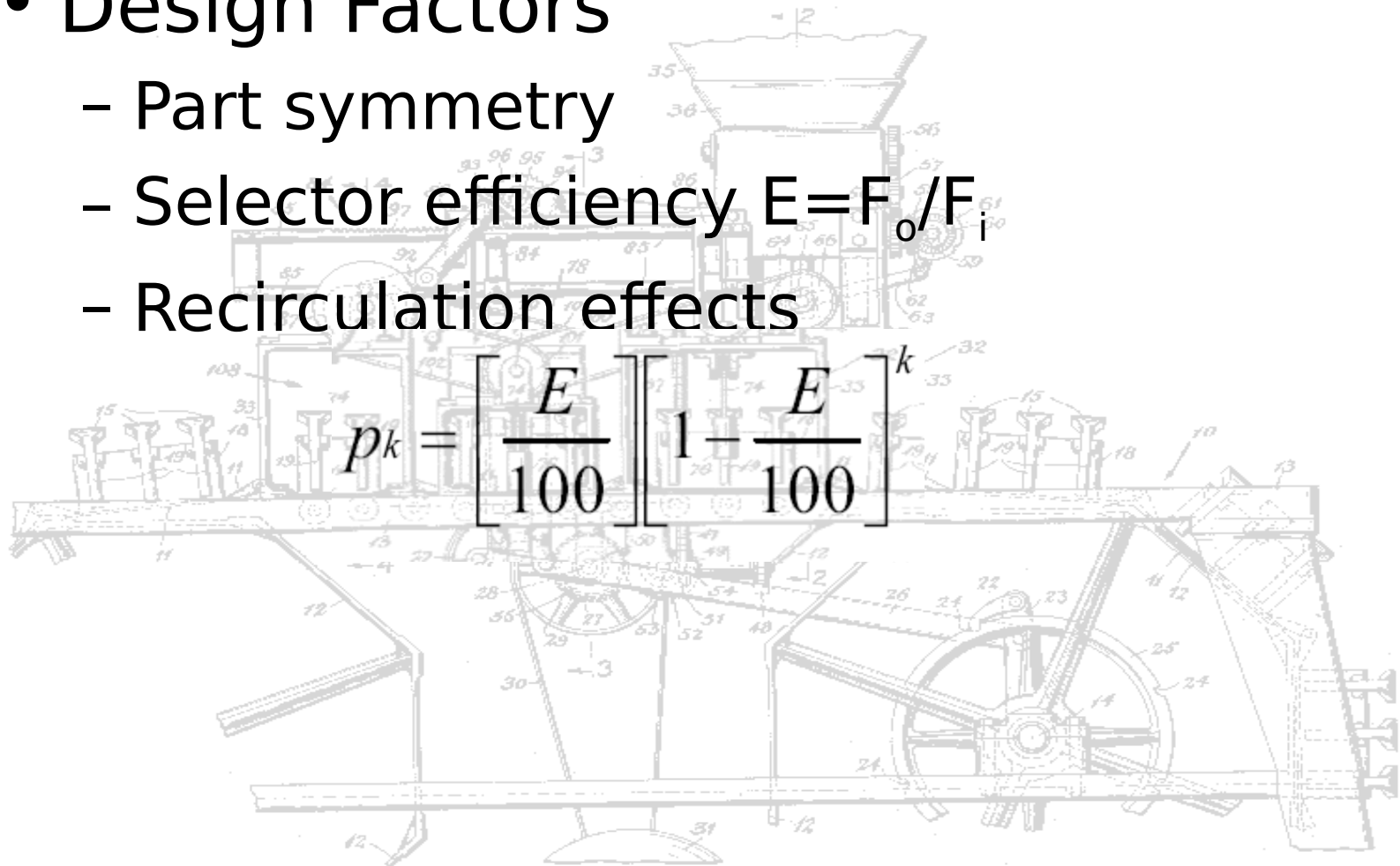


Bowl Feeders



Bowl Feeders

- Design Factors
 - Part symmetry
 - Selector efficiency $E = F_o / F_i$
 - Recirculation effects



Bowl Feeders - Trap Design

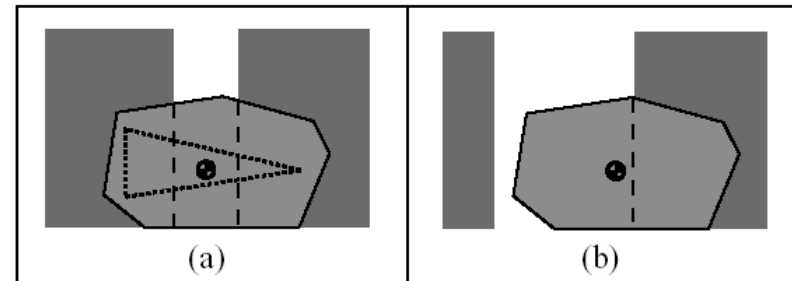
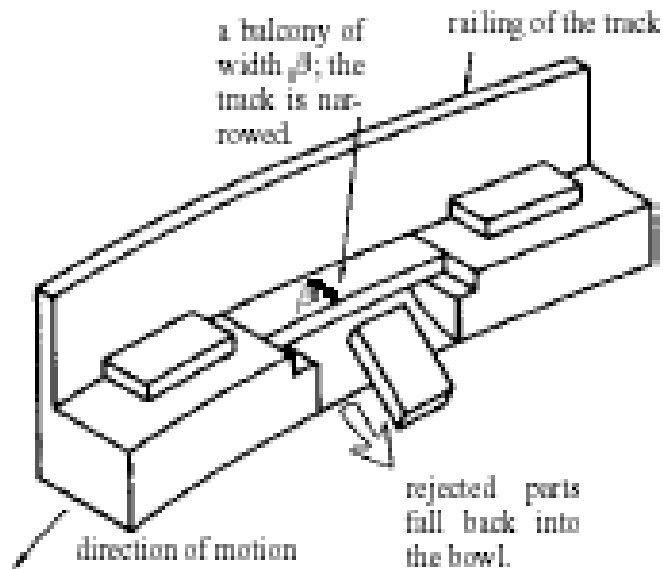


Figure 2: (a) A safe pose. The triangle is evidence of safety. (b) An unsafe pose of the same part above a different trap.

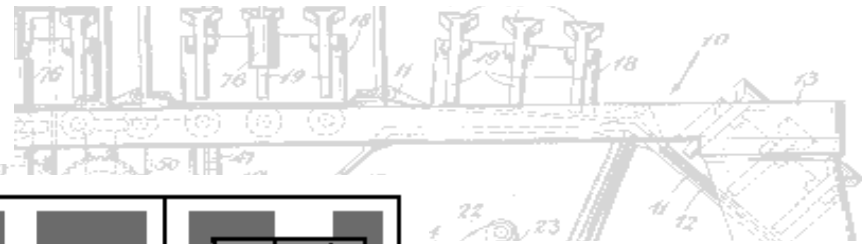
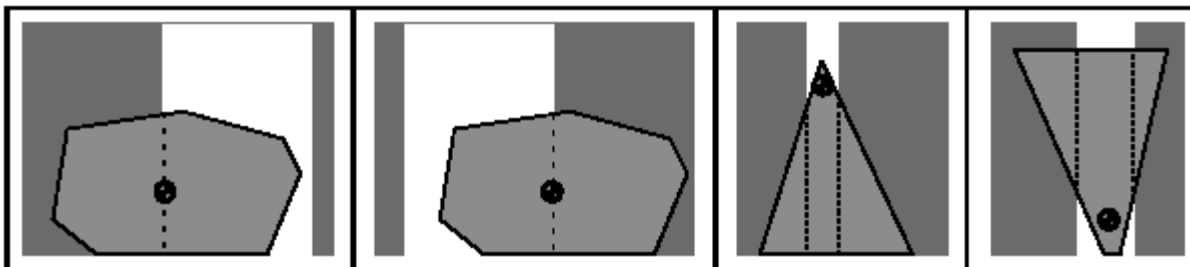


Figure 5: A critical pose.

Figure 4: The types of rejected poses.



Non-vibrating Feeders

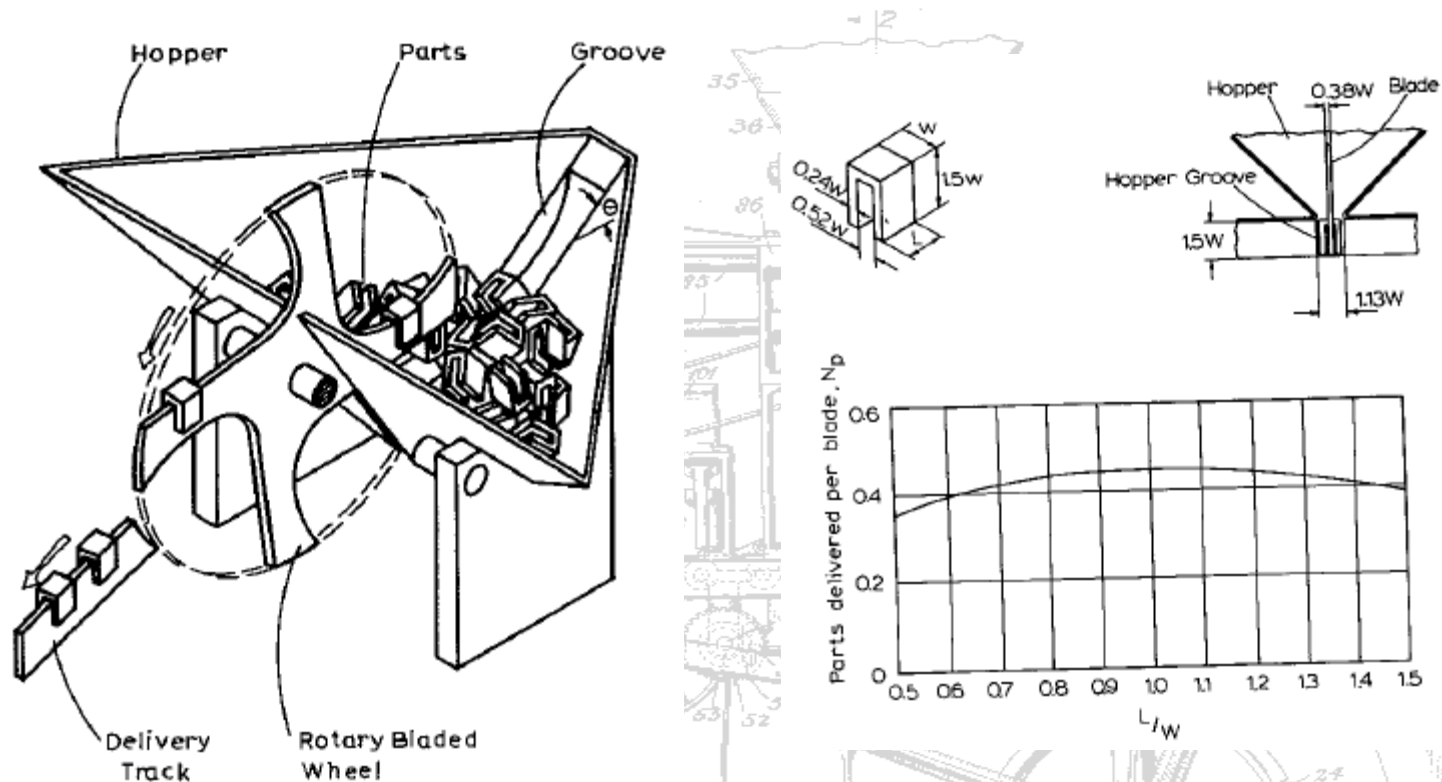


Fig. 4.34 Rotary centerboard hopper.

Non-vibrating Feeders

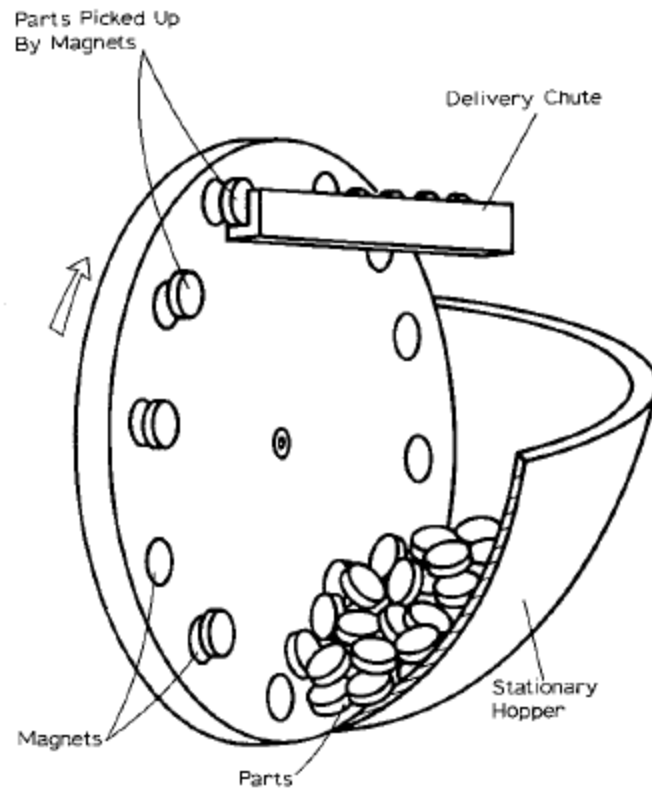
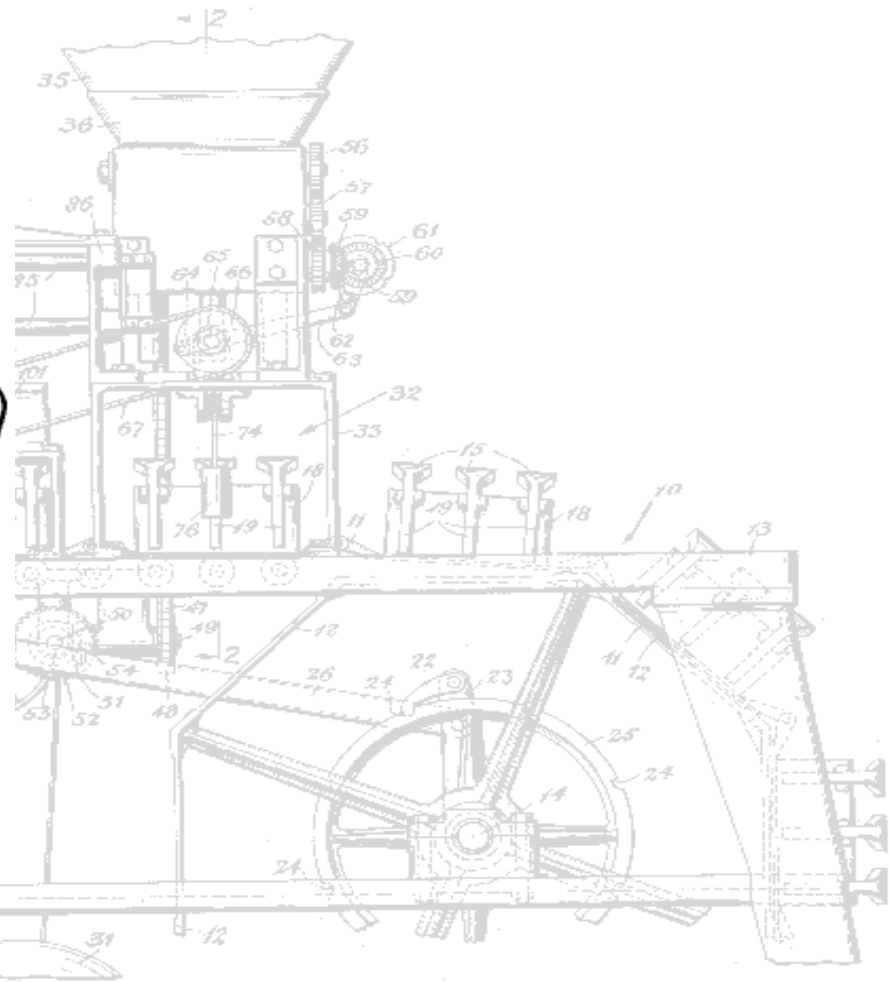
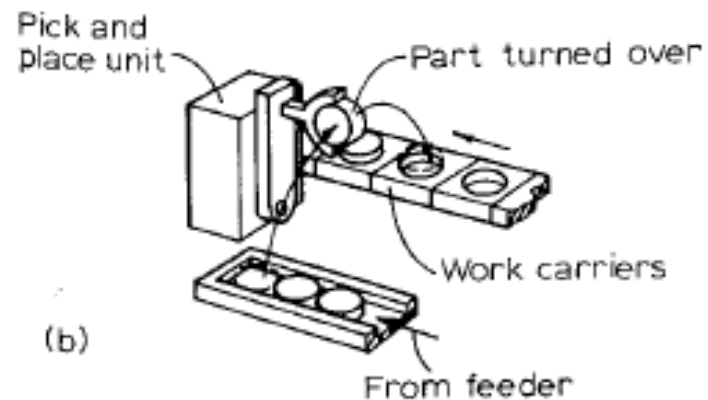
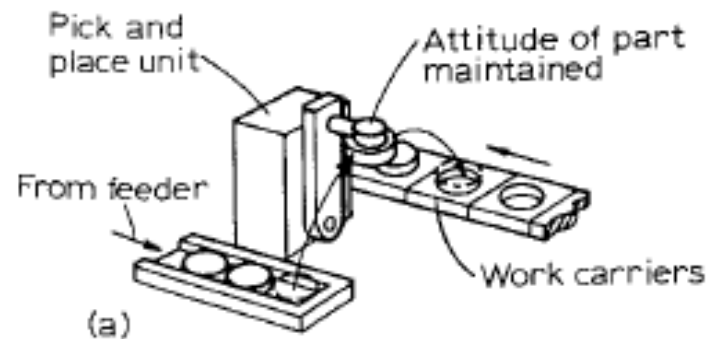
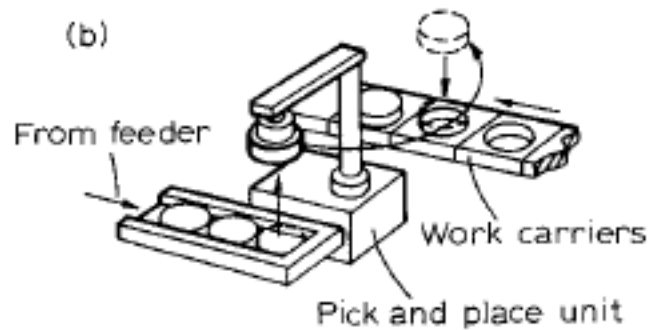
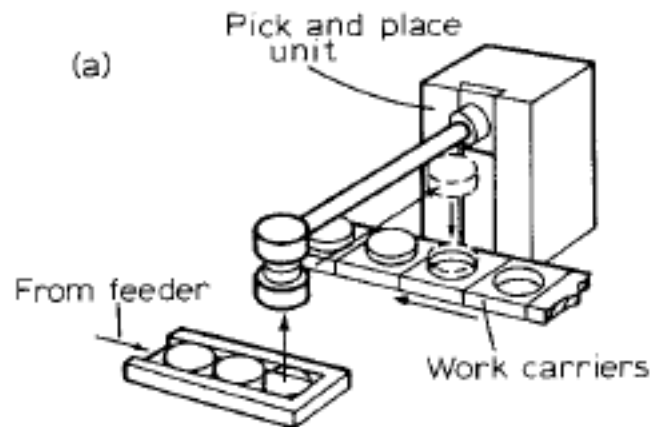


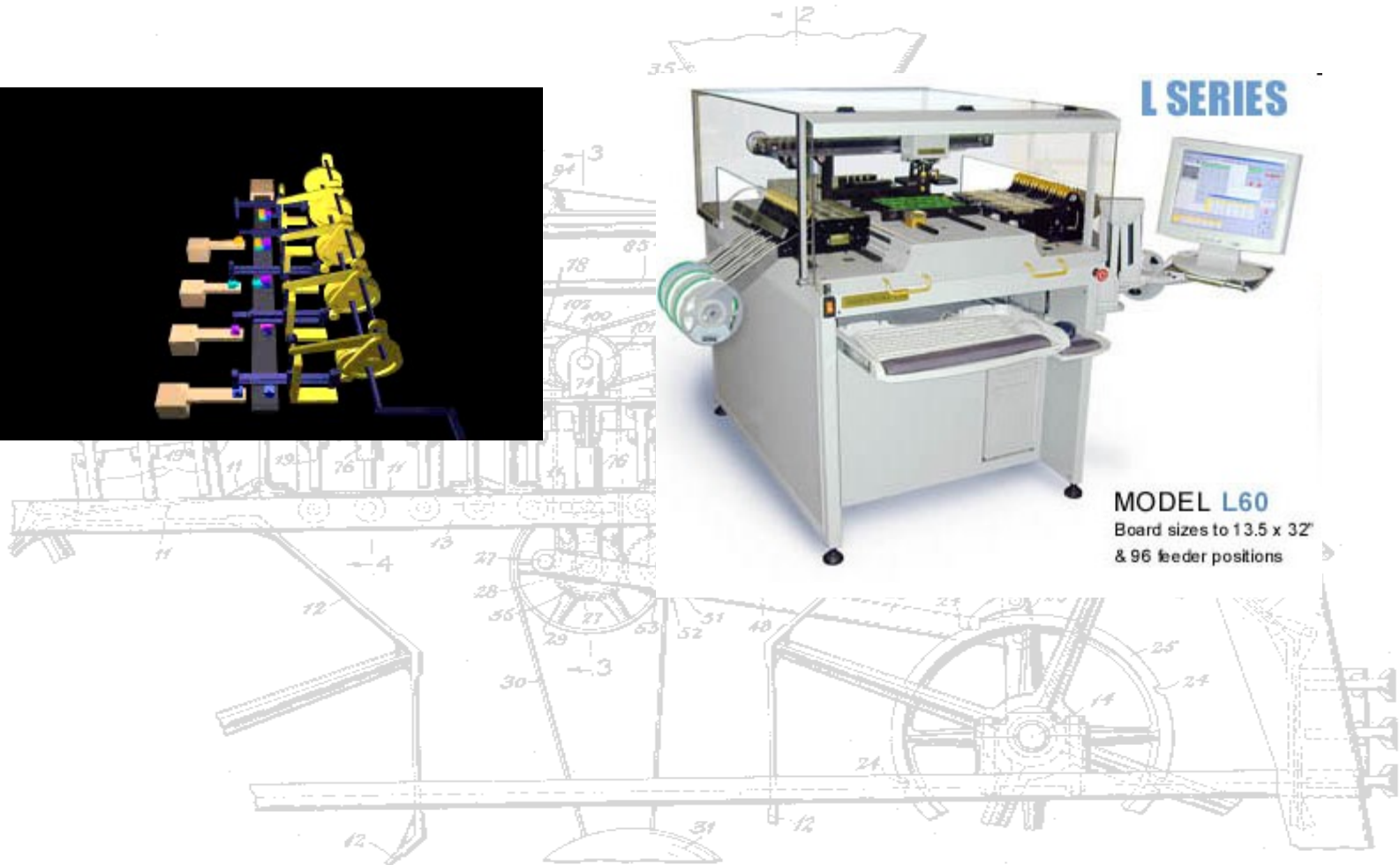
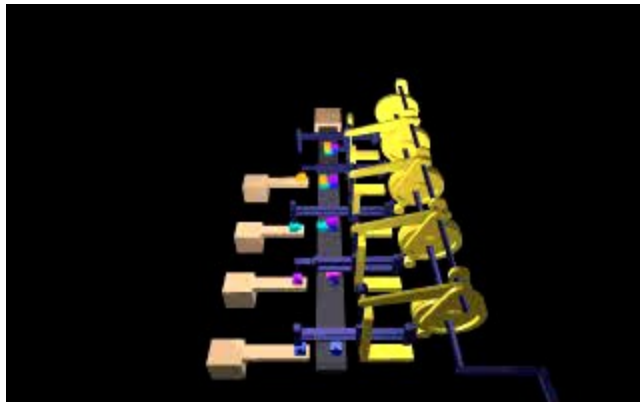
Fig. 4.36 Magnetic-disk feeder.



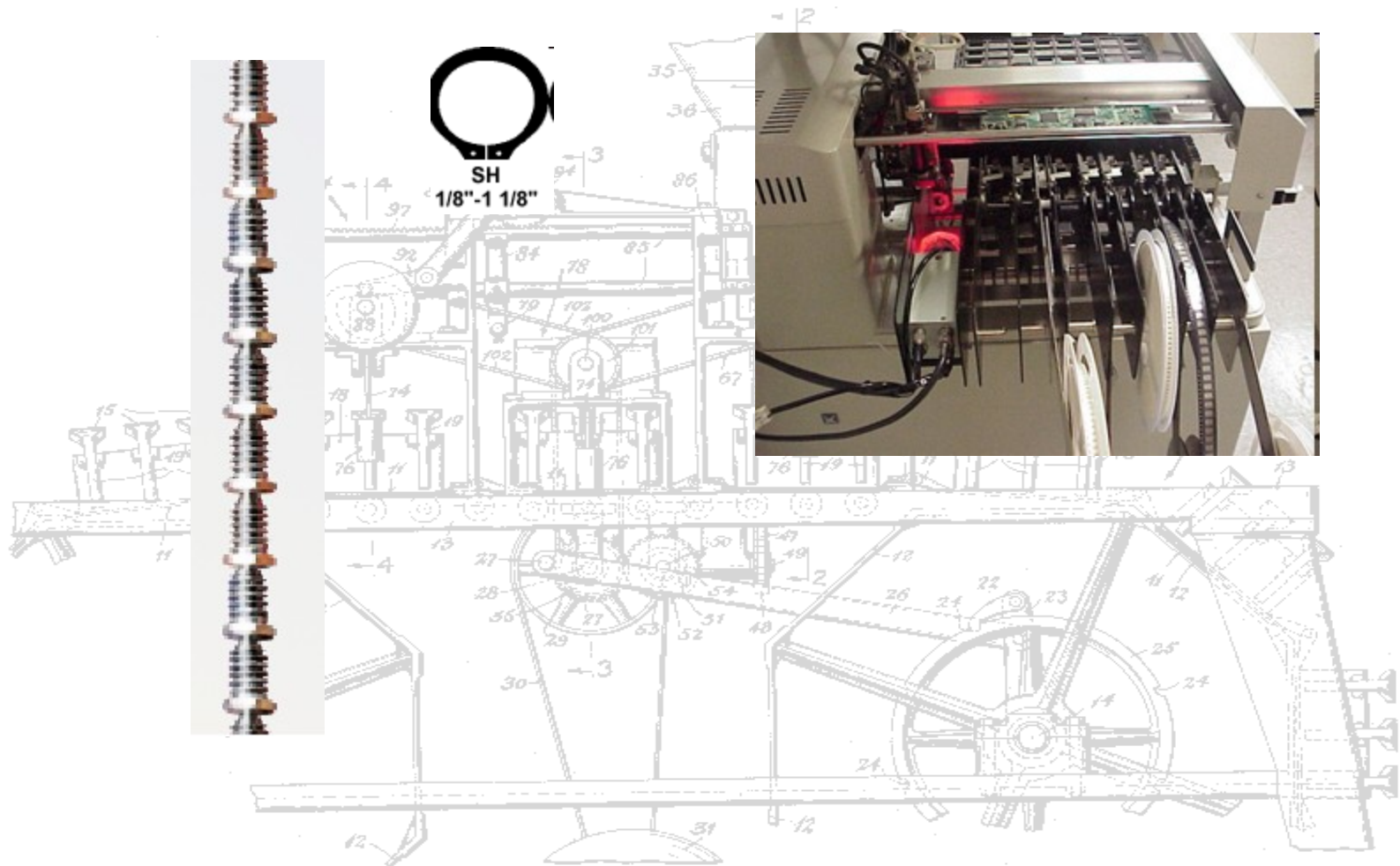
Pick & Place



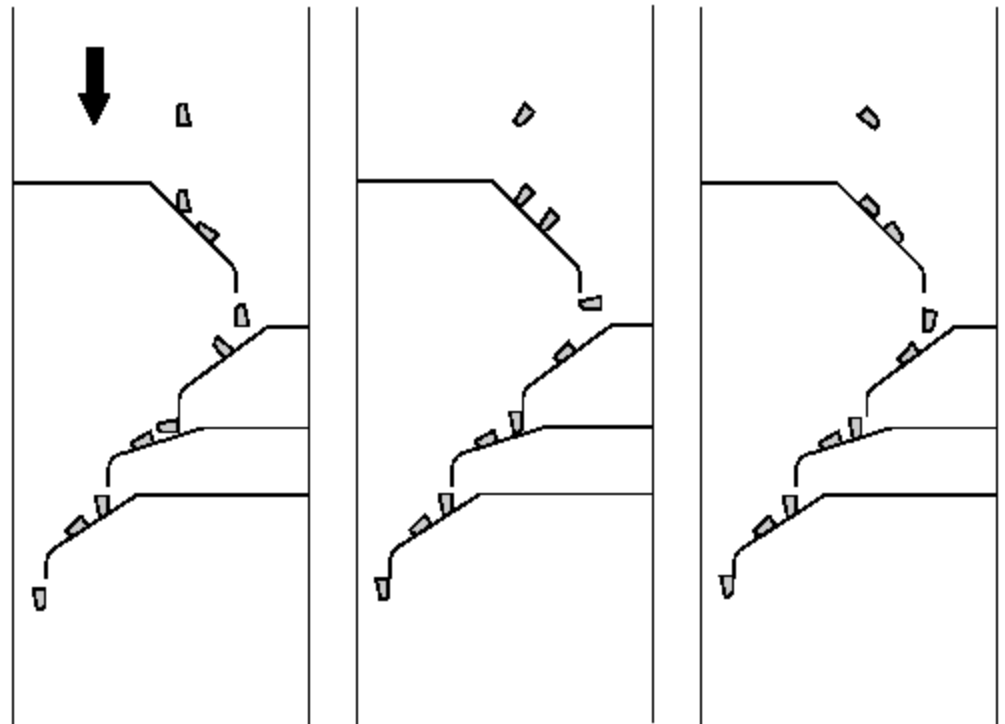
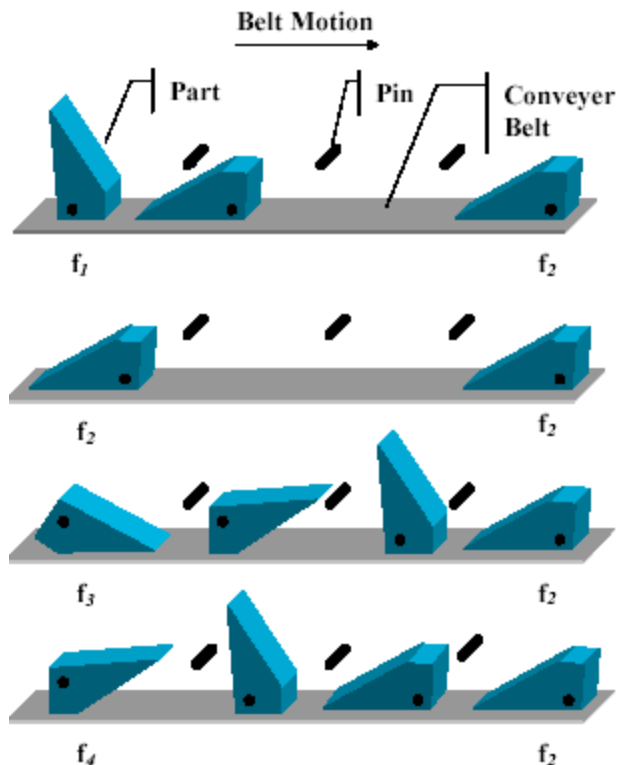
Pick & Place



Pre-collated Components



Conveyors



- Orienting with pins or fences

Conveyor part orientation - pins

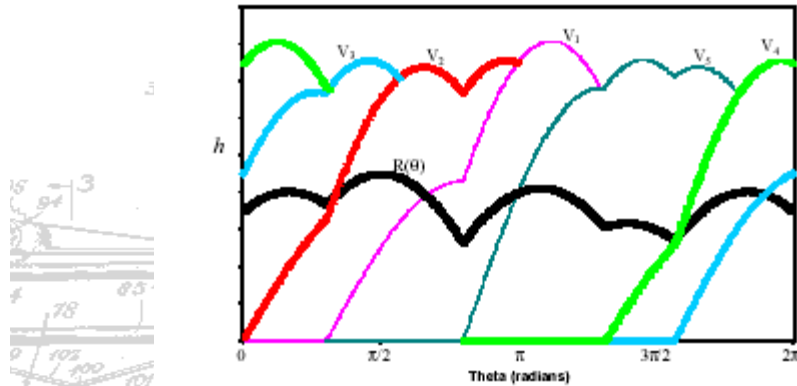
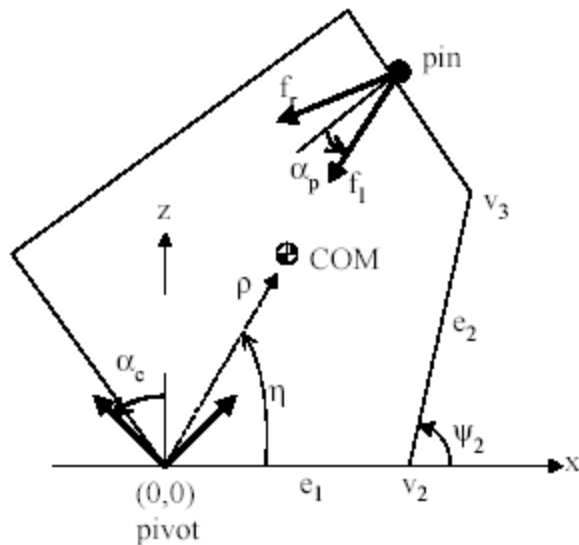


Figure 4. Radius function, $R(\theta)$, and vertex functions, $V_i(\theta)$.

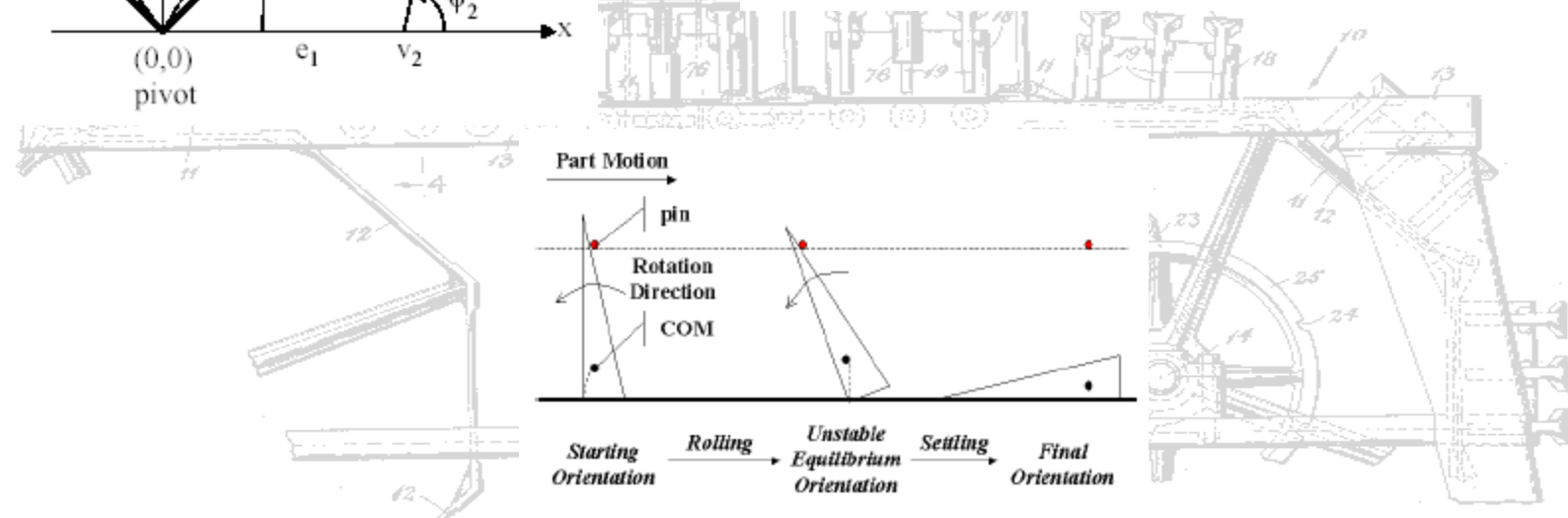


Figure 3. Two phases of toppling: *rolling* and *settling*.

Conveyor part orientation - pins

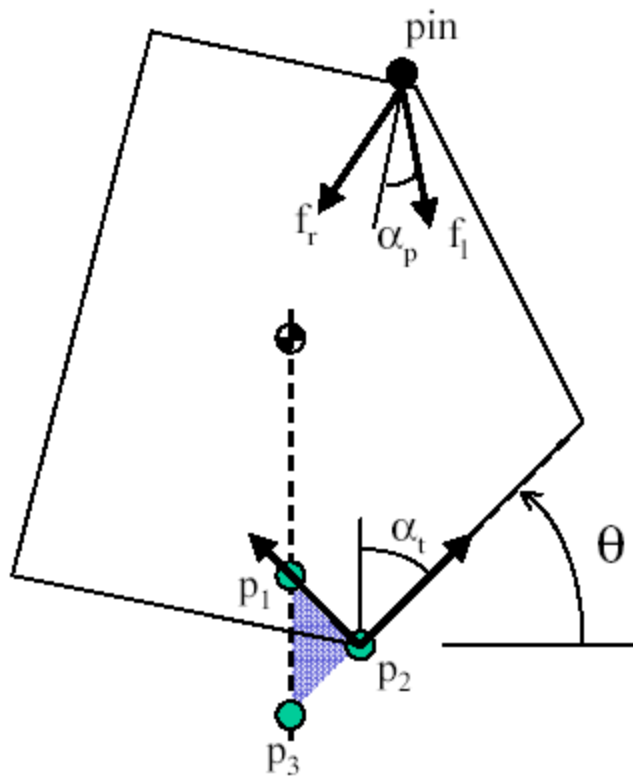


Figure 7. Jamming conditions.

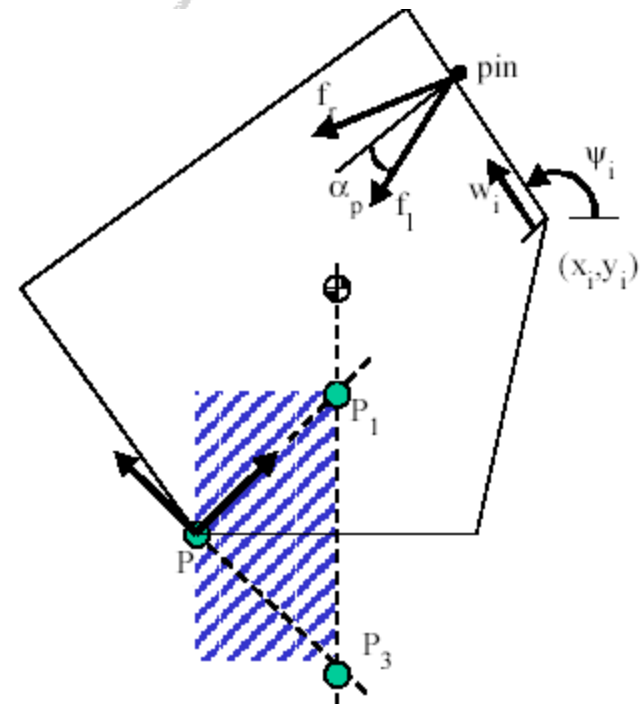
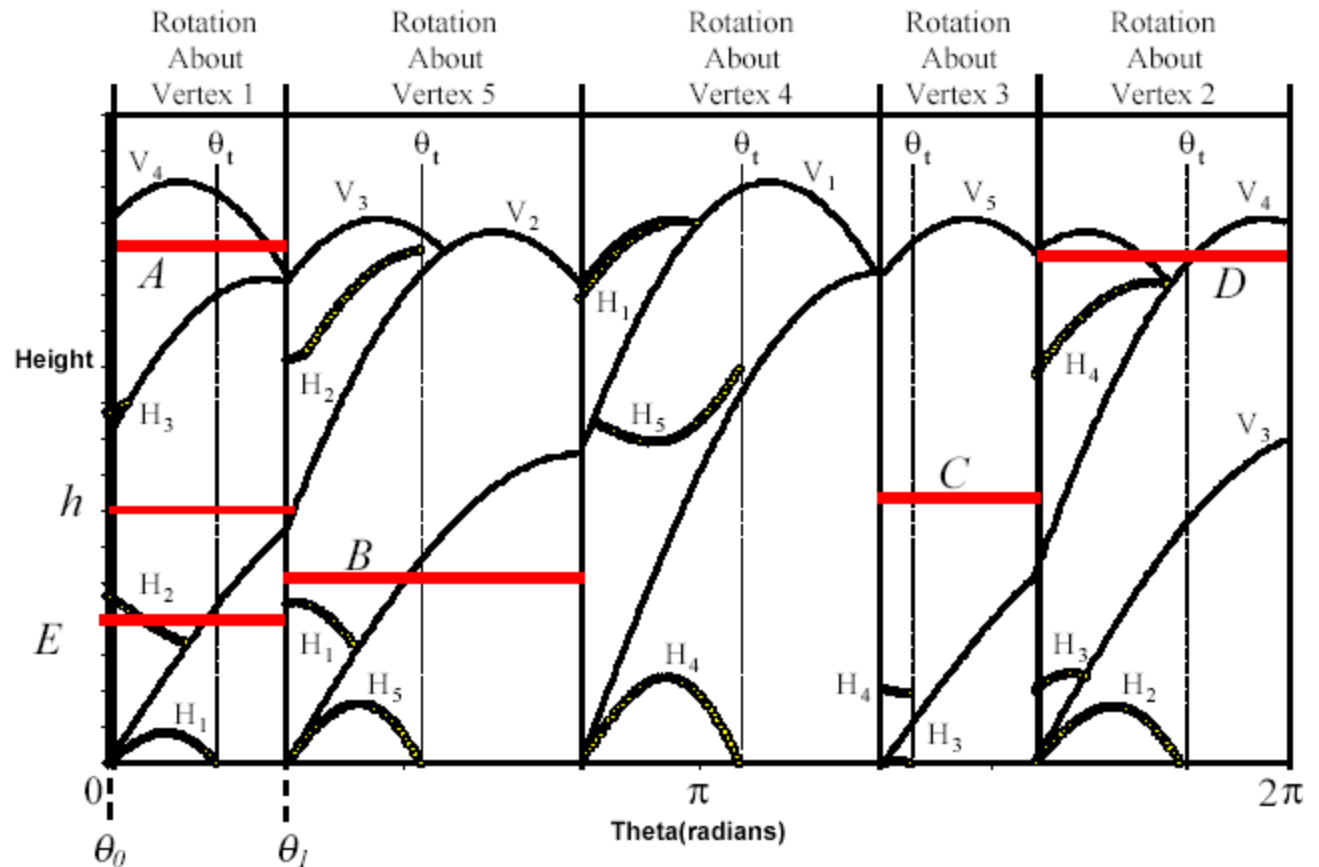
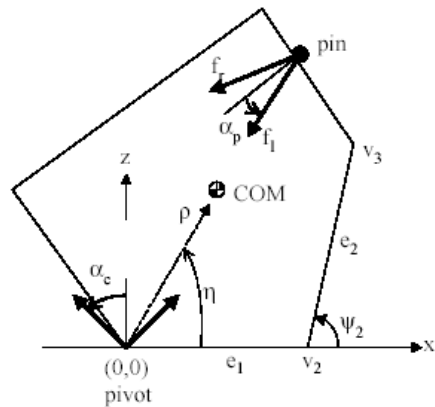


Figure 5. Conditions for the rolling phase.

Conveyor part orientation - pins



Conveyor part orientation - fences

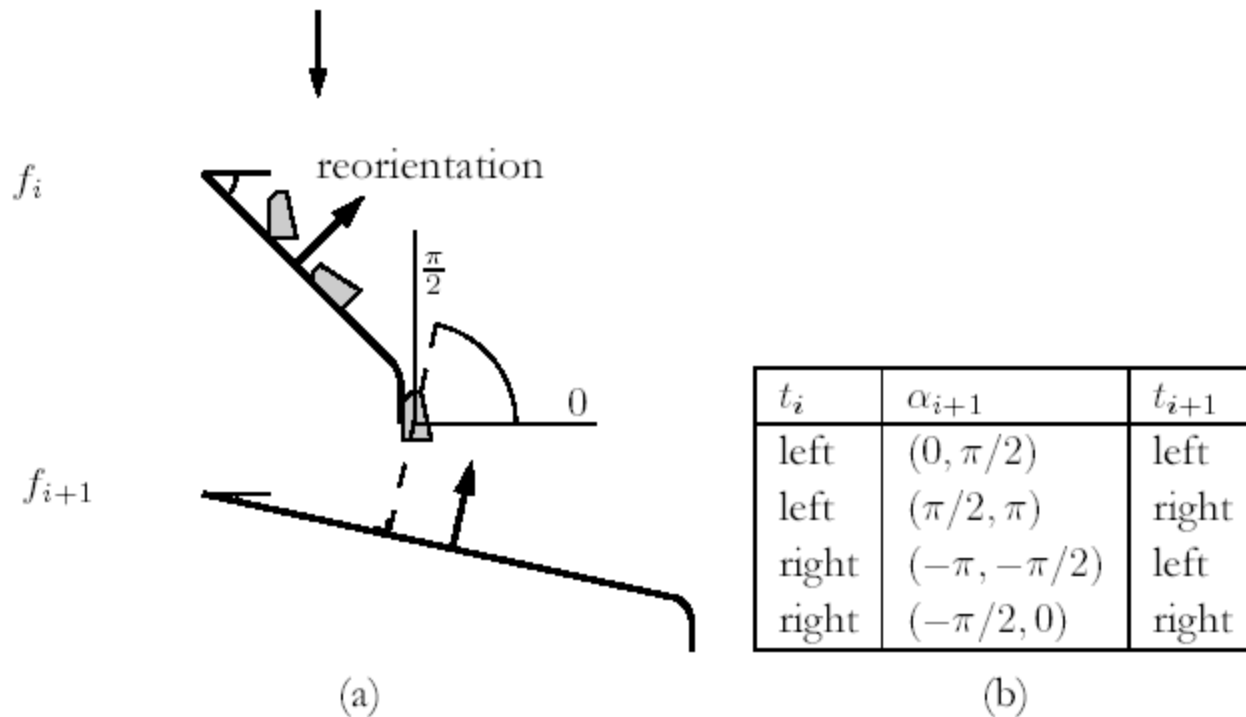
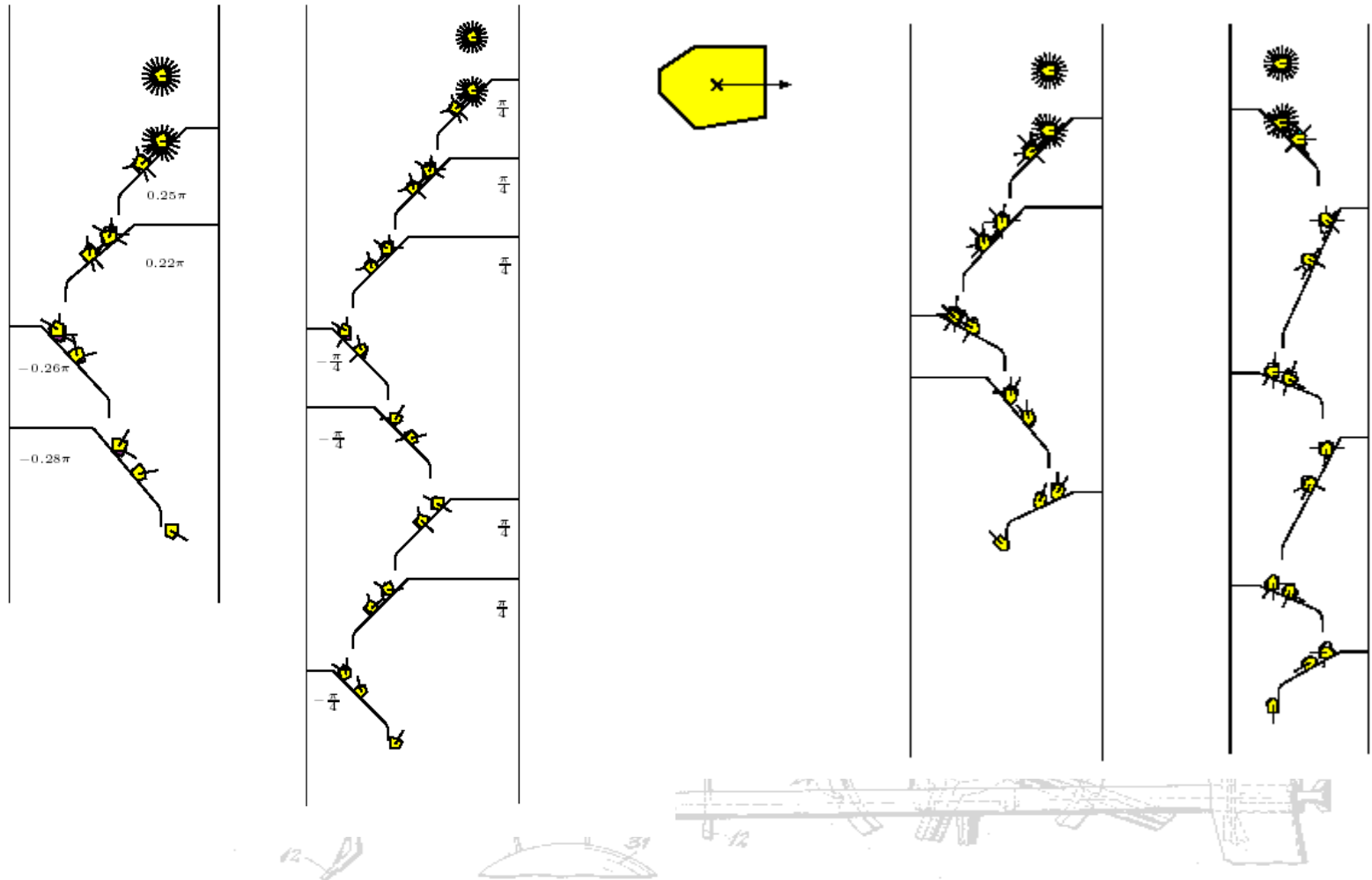


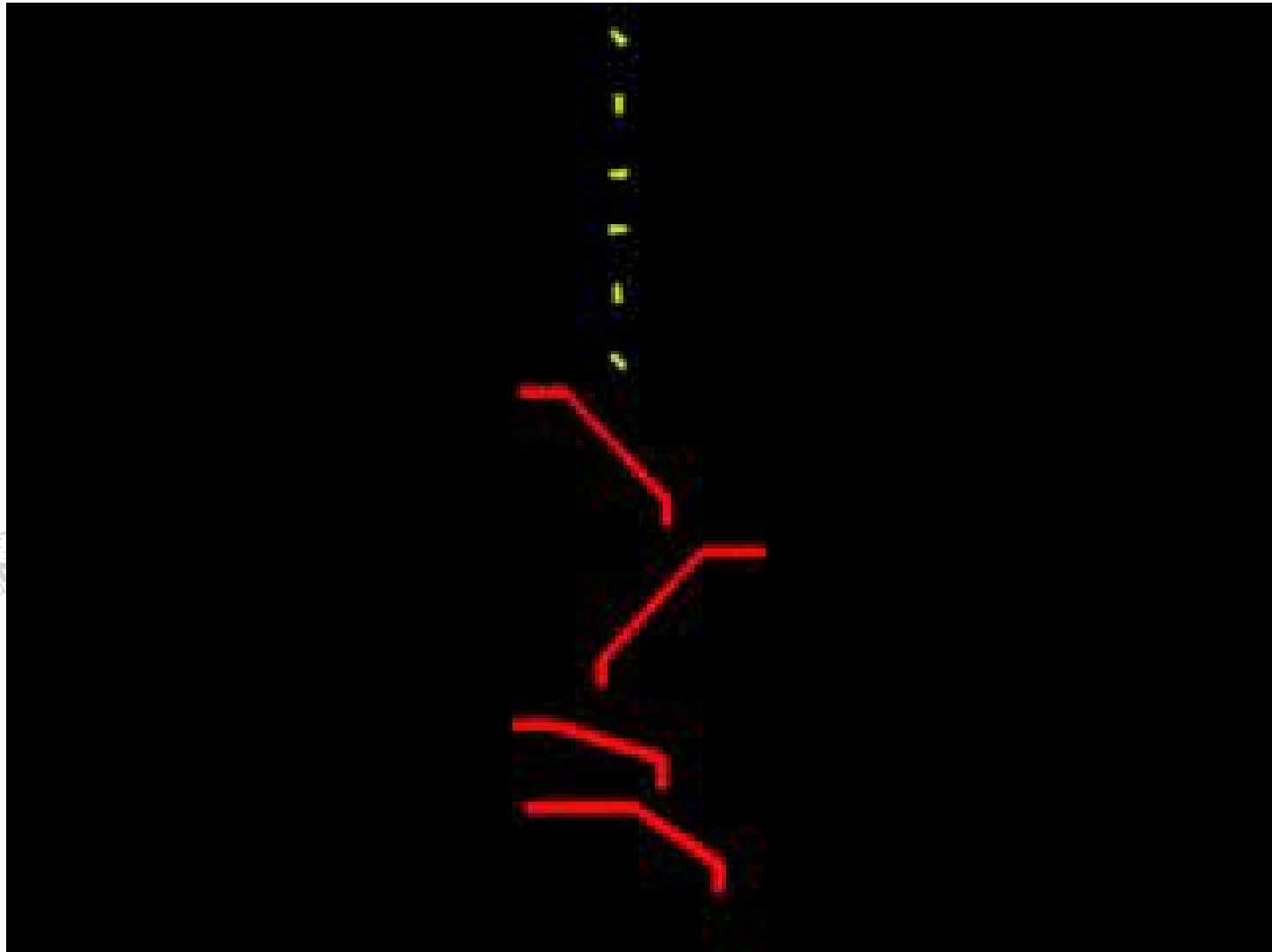
Figure 3.2 (a) For two successive left fences, the reorientation of the push direction lies in the range $(0, \pi/2)$. (b) The ranges of possible reorientations of the push direction for all pairs of fence types.

- Any polygonal part can be oriented up to symmetry by a fence design

Conveyor part orientation - fences



Conveyor part orientation - fences



Conveyor part orienting - 3D parts

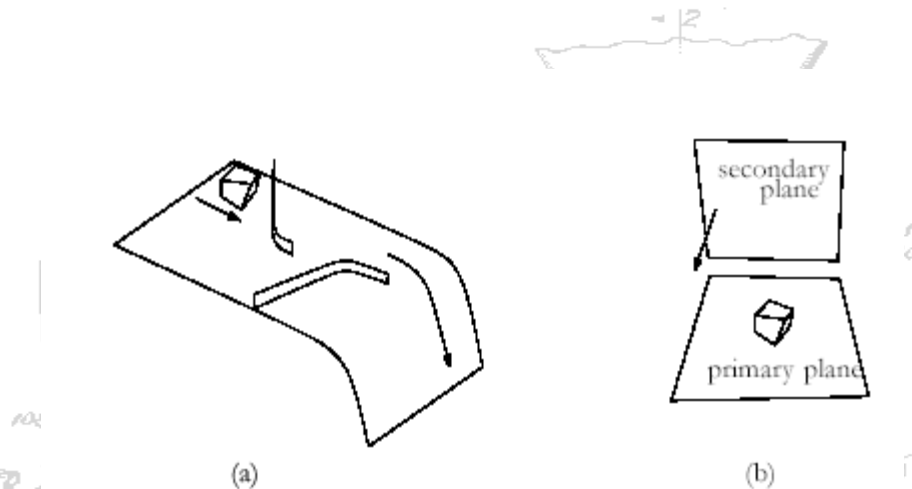


Figure 5.3 (a) A part sliding down a plate with fences. (b) The same part on the jaw.

