

# TEMM2018 CNME2018

Proceedings of the  
1<sup>st</sup> Iberic Conference on Theoretical and  
Experimental Mechanics and Materials  
&  
11<sup>th</sup> National Congress on Experimental  
Mechanics

(Porto/Portugal, 4-7 November 2018)

Editor

*J.F. Silva Gomes*

FEUP-INEGI  
(2018)

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## TABLE OF CONTENTS

Preface	xv
International Scientific Committee	xvi
Organizing Committee and Secretariat	xvi
Acknowledgments	xvi
<b>TRACK-A: EXPERIMENTAL TECHNIQUES AND INSTRUMENTATION</b>	<b>1</b>
7321 SYSTEM TO DETECT LEAKING IN FUEL ELEMENTS IN TRIGA NUCLEAR RESEARCH REACTOR. Amir Z. Mesquita, Rogério R. Rodrigues.	3
7328 RECENT ADVANCES ON EXPERIMENTAL DAM BREACH STUDIES. Sílvia Amaral, Teresa Alvarez, Laura Caldeira, Teresa Viseu, Rui Ferreira.	15
7333 ANÁLISE DA COMBUSTÃO EM UM MOTOR SI COM UM SISTEMA DE IGNIÇÃO COM PRÉ-CÂMARAS DE MISTURA HOMOGÊNEA. Vinícius R. Roso, Carlos E.C. Alvarez, Jose G.C. Baeta, Ramon M. Valle.	33
7343 ESTUDO DA RELAÇÃO ENTRE FRAÇÃO DE INJEÇÃO DE GÁS E DEFORMAÇÃO NO BOMBEIO CENTRÍFUGO SUBMERSO ATUANDO COM ESCOAMENTO BIFÁSICO. André A. Lima, Pablo S. Meirelles.	45
7347 EXPERIMENTAL IMPLEMENTATION OF A NUMERICALLY OPTIMIZED CONSTANT TEMPERATURE HOT-WIRE ANEMOMETER. José Neto, André Marandino, Laert Ferreira, Juliana Braga.	53
7349 TUBOS DE CALOR COM PÓ DE COBRE SINTERIZADO COMO ESTRUTURA CAPILAR: AVALIAÇÃO EXPERIMENTAL DA RAZÃO DE CARREGAMENTO. Larissa Krambeck, Guilherme A. Bartmeyer, Davi Fusão, Paulo H.D. Santos, Thiago A. Alves.	63
7350 TERMOSSIFÕES UTILIZANDO NANOFUIDOS DE OURO: INFLUÊNCIA DA INCLINAÇÃO DE TRABALHO NO COMPORTAMENTO TÉRMICO. Gedley K. Stremel, Larissa Krambeck, Vinícius M. Lenart, Rozane F. Turchiello, Thiago A. Alves.	75
7352 MONITORAMENTO DA QUALIDADE DO AR: AMOSTRAGEM DE MATERIAL PARTICULADO (MP2,5) EM PONTA GROSSA/BRASIL. Lucas V. Silva, Ricardo B. Nishida, Leonardo C. Melo, Ana F.L. Godoi, Ricardo H.M. Godoi, Thiago A. Alves, Yara S. Tadano.	85
7360 DESIGN OPTIMIZATION OF A NEW HETEROGENEOUS MECHANICAL TEST – NUMERICAL APPROACH AND EXPERIMENTAL VALIDATION. José Aquino, António Andrade-Campos, João M.P. Martins, Sandrine Thuillier.	95
7372 VALIDACIÓN EXPERIMENTAL DE UN MODELO MATEMÁTICO PARA LA DETERMINACIÓN DE LA FUERZA Y POTENCIA REQUERIDA EN LA COMPRESIÓN DE TALLOS DE CAÑA PANELERA. Alexander Díaz, Gabriel Calle, Ciro Iglesias.	97

7376	CARACTERIZAÇÃO DE PROPRIEDADES ELÁSTICAS DO TECIDO LENHOSO À ESCALA DOS ANEIS DE CRESCIMENTO PELO MÉTODO DOS ELEMENTOS FINITOS ITERATIVO. José Xavier, Luís Mota, João L. Pereira, José Morais.	109
7381	AVALIAÇÃO DO DESEMPENHO DE MEDIDORES PORTÁTEIS DE DESLOCAMENTO NA DETERMINAÇÃO DE PROPRIEDADES ELÁSTICAS DE MADEIRAS BRASILEIRAS. Rejane C. Alves, Edgar V.M. Carrasco.	113
7384	EXPERIMENTAL OUT-OF-PLANE BEHAVIOR OF TRADITIONAL BRICK MASONRY INFILL WALLS. Farhad Akhouni, Graça Vasconcelos, Paulo Lourenço, Carlos Palha, Luis Silva.	127
7388	ANÁLISE DO COMPORTAMENTO MECÂNICO DE UMA LIGAÇÃO DE MADEIRA SOLICITADA À FLEXÃO. Edgar V.M. Carrasco, Ana L.C. Oliveira, Judy N.R. Mantilla.	139
7399	INFLUENCE OF SALT CRYSTALLIZATION CYCLES IN THE COMPRESSIVE BEHAVIOR OF STONE MASONRY. Sandra Graus, Graça Vasconcelos, Carlos Palha.	141
7401	A NEW METHODOLOGY FOR DETECTION OF A LOOSE OR WORN BALL JOINTS USED IN VEHICLES SUSPENSION SYSTEM. Luis Carvalho, Sérgio Santos, Carlos Ferreira.	153
7402	PROPOSAL FOR AN EXPERIMENTAL STUDY OF THE THERMAL-HYDRAULIC PERFORMANCE OF NANOFLUIDS AS COOLANT IN LIGHT WATER NUCLEAR REACTORS (LWR). Alexandre M. Oliveira, Amir Z. Mesquita, Ênio P. Bandarra, Abdul O.C. Gómez, Lindomar M. Gonçalves.	159
7413	ENFRIAMIENTO DE TANQUES PREVIO A CARGA DE LÍQUIDO CRIOGÉNICO. Elmar Mikkelsen, Luis M. Mundo, Alejandro J. Patanella, Marcos D. Actis.	165
7417	DECISION TREE CLASSIFIER FOR PARAMETRIC FAULT DETECTION IN ELECTRICAL SUBMERSIBLE PUMPS. Mauricio B. Castellanos, Alberto L. Serpa.	167
7435	THERMAL CONDUCTIVITY OF CALCIUM SILICATE BOARDS AT HIGH TEMPERATURES: AN EXPERIMENTAL APPROACH. Thiago B. Oliveira, Thiago A. Alves, Luís M.R. Mesquita.	171
7437	MEASUREMENT AND SIMULATION OF THE SHIELDING EFFECTIVENESS OF MATERIALS USING THE ASTM D4935 FLANGED COAXIAL TRANSMISSION LINE. Hugo Tavares, Nelson Matos, Margarida Pinto, Guadalupe G. Gutiérrez.	183
7438	DYNAMICAL ANALYSIS OF A 230 kV TRANSMISSION LINE. Nilson Barbieri, Marcos J. Mannala, Lucas V. Barbieri, Gabriel V. Barbieri, Key F. Lima.	193
7439	PROTOTYPING AND CONTROL OF A ROBOTIZED EDUCATIONAL PLATFORM. Carlos Oliveira, José Gonçalves, João Ribeiro, Manuel T. Braz-César.	199
7440	DIDATIC METHODOLOGY TO CALIBRATE AN ULTRASOUND PHASED ARRAY SYSTEM. Júlia Soares, José Gonçalves, Manuel T. Braz-César, João Ribeiro.	201
7447	ON THE USE OF NON-HOMOGENEOUS THERMO-MECHANICAL FIELDS TO CHARACTERIZE DP980 STEEL SHEETS. J.M.P. Martins, S. Thuillier, A. Andrade-Campos.	203

PAPER REF: 7439

## **PROTOTYPING AND CONTROL OF A ROBOTIZED EDUCATIONAL PLATFORM**

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### **ABSTRACT**

This paper describes the prototyping of an educational kit based on a robotic arm and a conveyor belt. Initially, it was necessary to choose the structure to be used in the arm, develop its construction and carry some tests in order to know its mechanical limits. In order to perform a study of the workspace for the chosen robotic arm, the 3D modeling program Solidworks® was used. By using this software it is possible to design and carry out studies related to the arm, such as its workspace and mechanical limits. To move the arm, it are used servomotors, controlled by an Arduino. Thereafter, a structure for the conveyor belt has also been developed, so that the arm can work in conjunction with the conveyor. A DC motor is applied to move the conveyor and to detect the parts a distance measuring sensor is used.

**Keywords:** Robotic arm, conveyor belt, prototyping, servo motors, Arduino, DC motor.

### **INTRODUCTION**

Nowadays, more and more, the classes tend to involve more laboratory work. In this paper it is described the development of a low-cost platform with the purpose of its use in robotics education. Several educational robotic arms exist in the bibliography, such as the EasyARMDSmini, which is simple and inexpensive, constituted by 6 servo motors, providing 4 degrees of Freedom [1]. Another educational robotic arm is the Niryo One, a 6-axis anthropomorphic arm developed by *NIRYO*. This arm is printed in 3D, has a weight of 3.2 kg and supports 500g, its repeatability being approximately 1mm [2].

### **RESULTS AND CONCLUSIONS**

Considering the study carried out, it was chosen to be developed a manipulator with 3 degrees of freedom. The components of the robotic arm were printed in 3D. Once printed, for the arm to operate it was necessary 3 servo motors, each one for each degree of freedom, and a micro servo motor capable of opening and closing a claw, which is the end effector. These servo motors are controlled by the Arduino. The conveyor was developed through the SolidWorks geometric modeling program, a software that allows for prior planning and the choice of the best possible design. Once the pieces are developed, it are 3D printed. In the conveyor prototyping, it was chosen not to use bearings, in order to reduce the cost. A joint system has been created, and a part that is not centered can be routed through this system. To detect the parts, a SHARP infrared sensor was chosen and a 19:1 DC motor was used to move the conveyor belt.

Through the whole procedure it was obtained the desired model. After the connections were made, a controller was developed in the Arduino that was used to operate the final model, as shown in Figure 1.

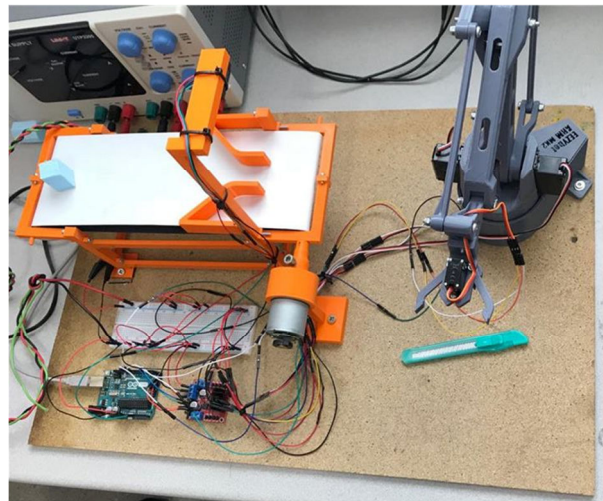


Fig. 1 - Final Model.

The developed controller has the purpose, initially, to transport a material part towards the robot workspace. Once the part is detected, the conveyor will stop, and the robotic arm will be activated, moving towards the piece. When the arm reaches the part, it will grab it, and move it to the free corner of the educational kit, which was previously defined. When it arrives at the destination, it drops the piece, it will be in rest position and the conveyor will be activated again.

With the work done, it was concluded that Solidworks® is a very complete and important program nowadays. Through this it is possible to carry out a previous planning, to carry out studies and to opt for the best possible design. Concerning Arduino, it was a great bet because it uses an a low-cost development board that it is used by an enormous and very active community. Through this it was possible to control, the DC Motor, the servo motors and to get the Sharp sensor reading. The used library was Braccio, being possible to control up to 6 servo motors. Through this library it is possible to vary the speed with which the arm executes the movements, since it allows to vary the time between the movement of each servo between 10 and 30ms. The use of servo motors in precision work is an excellent option as they are very precise components. The use of the DC motor to move the conveyor belt was also a successful approach, although it presents some difficulty in moving, because it has no bearings and thus have a lot of friction, the engine has overcome the specs because the conveyor belt moves very well. The choice of arm and carpet to be printed in 3D has proved to be an excellent choice as the material provides great resistance and presents a low cost. Whenever a piece is printed in 3D, one must consider its wholes and its faces, because of this type of printing sometime presents some imperfections, and it is necessary an inspection and repair.

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[2]-website: <https://www.kickstarter.com/projects/niryo/niryo-one-an-open-source-6-axis-robotic-arm-just-f>.