A Volumetric Contact Model for Space Robot and Planetary Rover Application

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Outline

1. Introduction
2. Elastic Foundation Model
3. Experimental Validation
4. Hyperelastic Foundation Model
5. Planetary Rover Simulation Platform
6. Future Work

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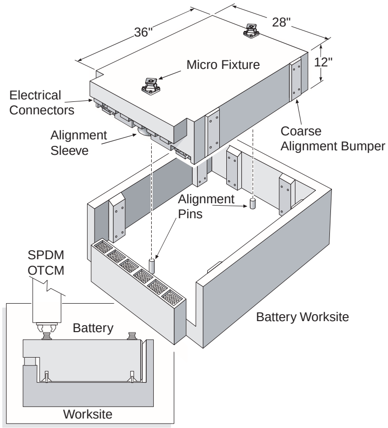
Motivation

Figure: Dextre at the tip of Canadarm2 (Gonthier, 2007).

Contact Models



ISS battery box (Gonthier, 2007).

Point contact models

- Small contact patches only
- Simple, convex geometries
- No rolling resistance, spinning friction torque

FEM

- Too complex for real-time

Contact Models

Falling ISS battery box:
real-time (Gonthier, 2007)

Point contact models

- Small contact patches only
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- No rolling resistance, spinning friction torque

FEM

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Volumetric contact model

Advantages

- Larger, more complex, and conforming contact patches possible
- Includes both translational (normal and friction forces) and rotational (rolling resistance and spinning friction torque) dynamics.

Volumetric contact model

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- Validation of the model still required for hard contact (metals)

Goals

1. Experimentally validate the normal force components of the volumetric contact dynamics model for hard-on-hard (metal) contact
2. Demonstrate parameter identification for this model

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Volumetric model

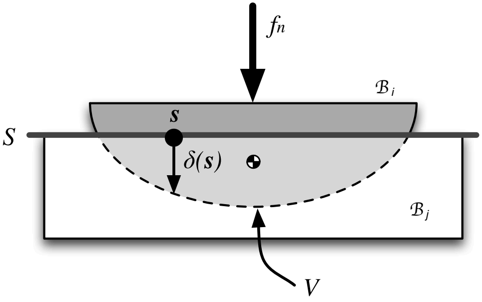
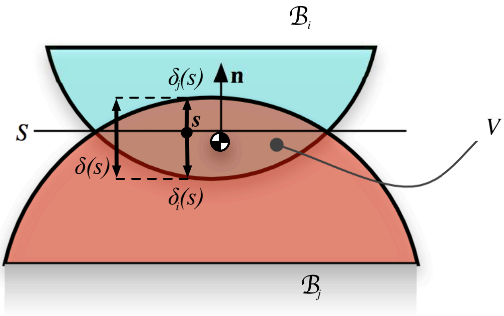


Figure: A volumetric contact model based on a Winkler foundation.

$$p(\mathbf{s}) = \frac{df_n}{dS} = k_v \delta(\mathbf{s})(1 + a v_n)$$

Volumetric properties



Volumetric properties

V - volume of interference

n - contact normal

$\mathbf{J}_S$ - surface-inertia tensor

$\mathbf{J}_V$ - volume-inertia tensor

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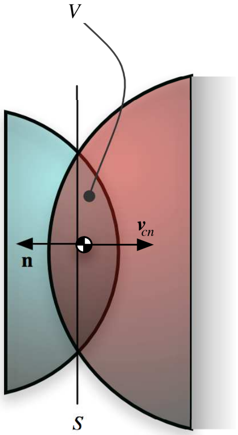
Normal forces



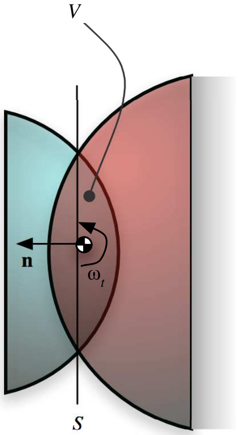
Normal force

$$\mathbf{f}_{\mathrm{n}} = k_v V(1 + a v_{cn})\mathbf{n}$$

Rolling resistance

Rolling resistance torque

$$\boldsymbol{\tau}_{\mathrm{r}} = k_{\mathrm{v}}\, a\, \mathbf{J}_{\mathrm{s}} \cdot \boldsymbol{\omega}_{\mathrm{t}}$$



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Friction

The model can include tangential friction forces and spinning friction torque.

Friction forces (Gonthier et al., 2007)

$$\mathbf{f}_{\mathrm{t}} = -\mu_c f_{\mathrm{n}} \frac{\mathbf{v}_{\mathrm{ct}}}{v_{\mathrm{avg}}}$$

$$\boldsymbol{\tau}_{\mathrm{s}} = -\frac{\mu_c f_{\mathrm{n}}}{V v_{\mathrm{avg}}} \mathbf{J}_{\mathrm{s}} \cdot \boldsymbol{\omega}_{\mathrm{n}}$$

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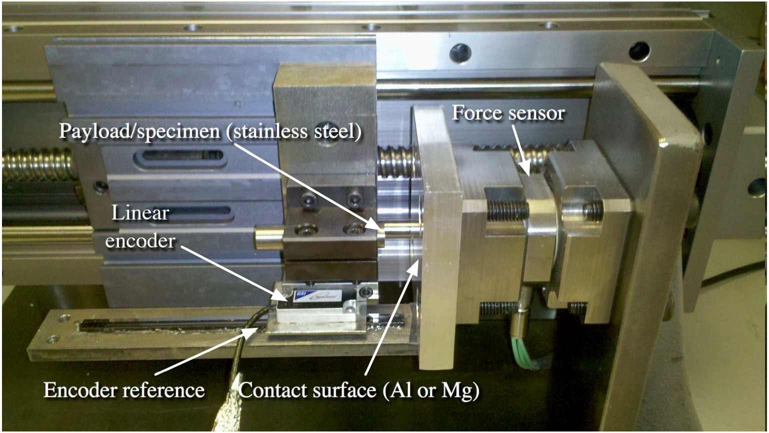
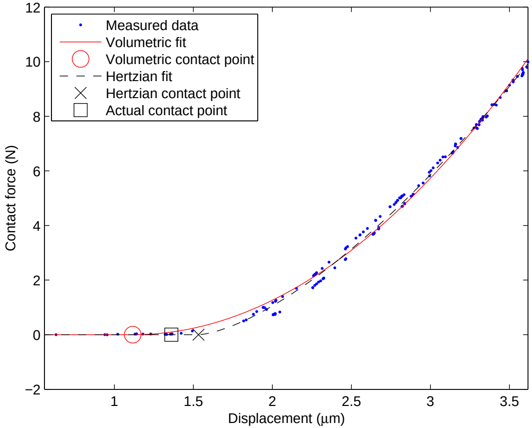
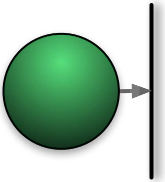
Apparatus in normal configuration



Quasi-static results with sphere on aluminum

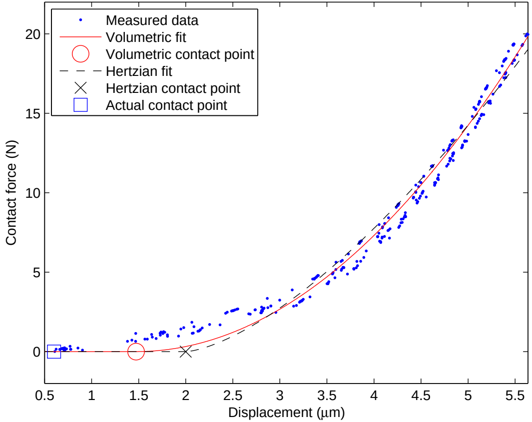




Volumetric stiffness

$$k_v = 7.59 \times 10^{13} N/m^3$$

Quasi-static results with sphere on magnesium



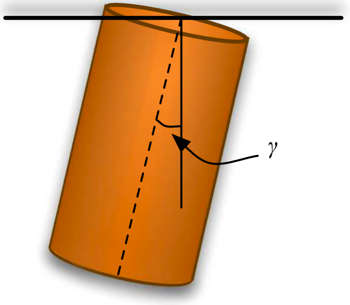
- Magnesium surface tarnished quickly after polishing
- Orthotropic material

Volumetric stiffness

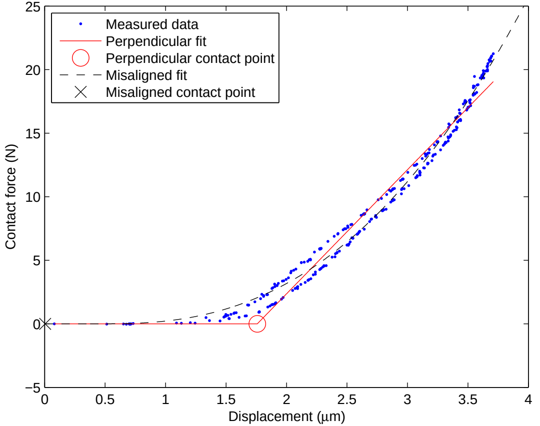
$$k_v = 3.82 \times 10^{13} N/m^3$$

Cylinder-on-plane contact

- Non-linear force-displacement relationship
  - Either misalignment or surface asperities
- Used a cylindrical wedge to estimate possible misalignment for the volumetric model



Quasi-static results with cylinder on aluminum



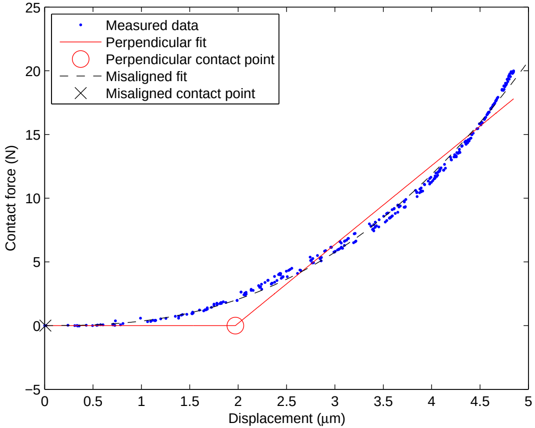
Theoretical volumetric stiffness

$k_v = 8.82 \times 10^{12} N/m^3$

Estimated misalignment

$\gamma = 0.32^\circ$

Quasi-static results with cylinder on magnesium



Theoretical volumetric stiffness

$k_v = 5.17 \times 10^{12} N/m^3$

Estimated misalignment

$\gamma = 0.46°$

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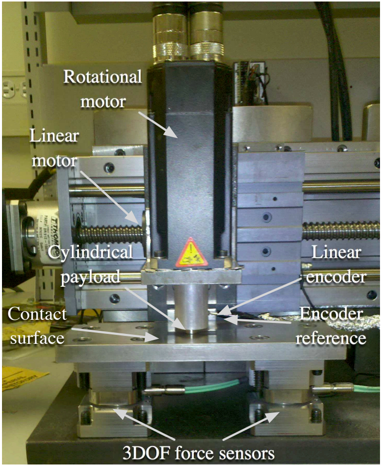
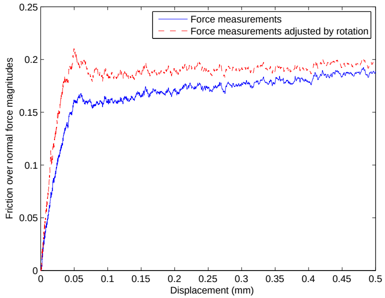
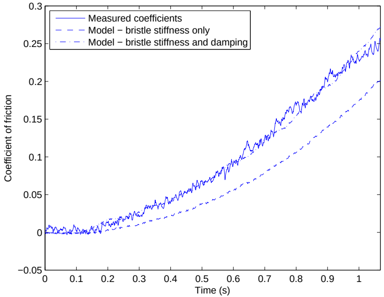
Apparatus in friction configuration



Static friction for translation





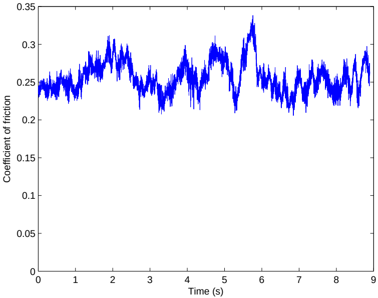
Coefficient of static friction

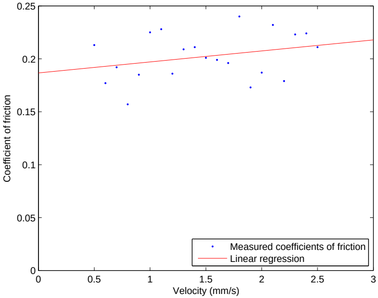
$\mu_s \approx 0.2$

Bristle stiffness and damping

$\sigma_0 = 4500 m^{-1} \quad \sigma_1 = 300 s/m$

Kinetic friction for translation

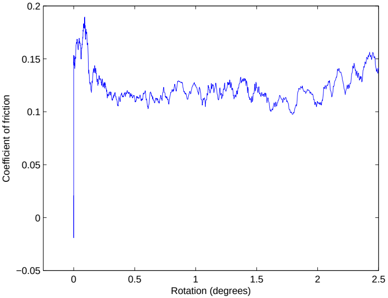


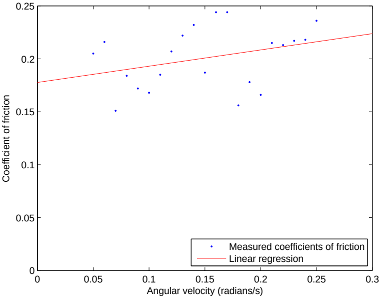


Coefficient of kinetic friction

$\mu_d \approx 0.2$

Rotation experiments





Coefficient of static friction

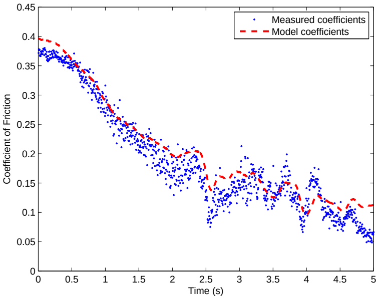
$\mu_s \approx 0.2$

Coefficient of kinetic friction

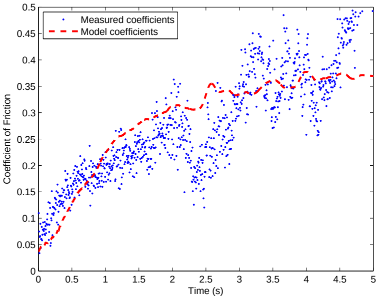
$\mu_d \approx 0.2$

Conensou effect experiment

Tangential force measurements



Spinning torque measurements



Key findings

- Normal contact
  - Experiments compare well against Hertzian models
  - Applicability to unusual geometries demonstrated
  - Inverse relationship between impact velocity and damping

Key findings

- Normal contact
  - Experiments compare well against Hertzian models
  - Applicability to unusual geometries demonstrated
  - Inverse relationship between impact velocity and damping
- Friction contact
  - Similar results for translation and rotation
  - Adhesion effect observed
  - Contensou effect demonstrated

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Motivation for Hyperelastic Foundation

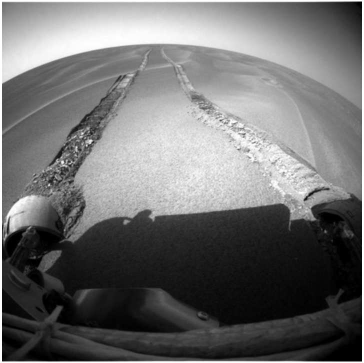
Tire Model for Planetary Rover Simulation

Off-Road Tire Models

- Rigid/Flexible wheel
- Soft soil

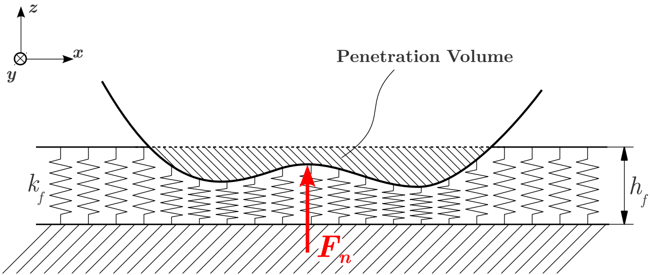
Contact Modelling

- Soft-soft contact
- Large deformation
- Highly nonlinear soil properties



Hyperelastic foundation model is required

Volume vs. Hypervolume



Elastic Foundation:

$$\mathbf{F}_{n,L} = k_v \underbrace{\int f_S(\mathbf{S})\, dS}_{\text{Volume } V} \mathbf{n}$$

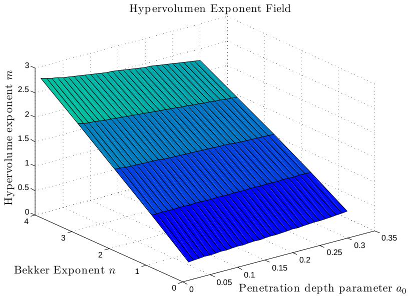
Hyperelastic Foundation:

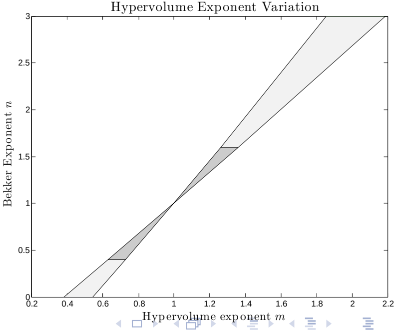
$$\mathbf{F}_{n,NL} = k_v \underbrace{\int f_S^n(\mathbf{S})\, dS}_{\text{Hypervolume } V_h} \mathbf{n}$$

Cylinder on Flat Ground

Exact Solution: Find m for a variation of n

$$\int f_S^n(\mathbf{S})\, dS - V^m = 0$$



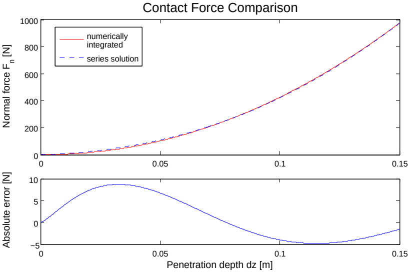


Cylinder on Flat Ground

Series Solution: Find α_i for a certain n and $dz = 0..R$

For $n > 1$:

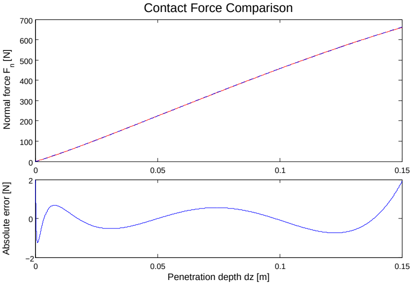
$$\int f_S^n(\mathbf{S})\,dS - \sum_{i=1}^{4} \alpha_i\, V^i = 0$$



Error: 1.38%

For $n < 1$:

$$\int f_S^n(\mathbf{S})\,dS - \sum_{i=1}^{8} \alpha_i\, V^{1/i} = 0$$



0.129%

Cylinder on Flat Ground

Mean Value Solution: Find $c_v(V)$ for a variation of n

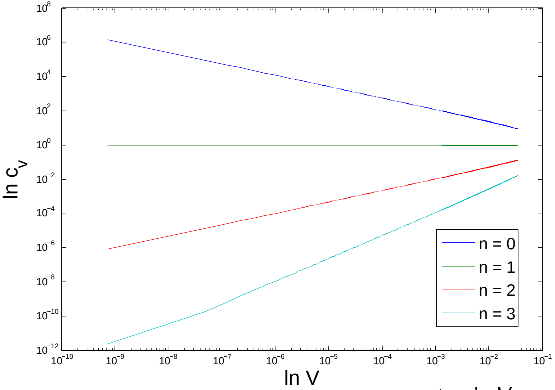
$$\begin{aligned} F_{n,NL} &= k_v b \int_{-a}^{a} g(x)^n \, dx \\ &= k_v b \int_{-a}^{a} g(x)^{(n-1)} g(x) \, dx \end{aligned}$$

Apply 'Mean Value Theorem'

$$\begin{aligned} F_{n,NL} &= k_v b c_v(V) \int_{-a}^{a} g(x) \, dx \\ &= k_v b c_v(V) V \quad \text{with} \quad c_v(V) = \frac{\int_{-a}^{a} g(x)^n \, dx}{\int_{-a}^{a} g(x) \, dx} \end{aligned}$$

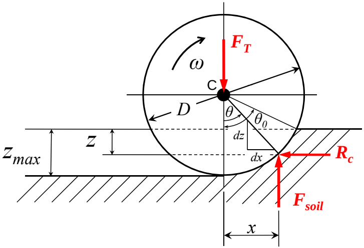
Cylinder on Flat Ground

Results of $c_v(V)$ for wheel with $R = 0.15$



$$\text{Possible Solution :} \quad c_v(V) = e^{a_0 + a_1 \ln V}$$

Tire/Soil Contact Model



- Vertical Force:
  - Hyperelasic foundation model
  - Bekker soil parameters
- Longitudinal Force:
  - Traction force (Janosi-Hanamoto, grousers)
  - Resistance force (soil compaction)

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Planetary Rover Model

Juno Rover MPEG

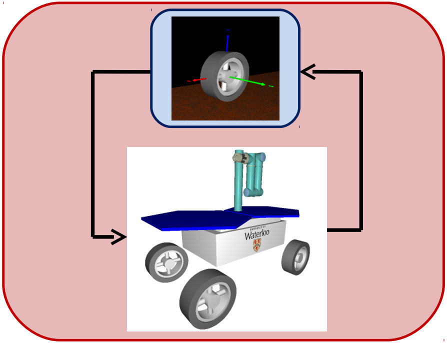
- Developed MapleSim 4.5 Model
- Exported symbolic equations to S-function block
- Developed Simulink model and with LLG contact models

Planetary Rover Simulation Platform

Combine tire model with rover dynamics

MuT (Multibody Toolbox)

Contact Model
Libraries
in
Numeric Simulation
Environment



Planetary Rover Simulation

Simulation and animation of rover with Parallel Geometry Inc. (LLG) software

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Future work

1. Experimental validation of hyperelastic contact models

2. Use more sophisticated tire and terrain geometries

3. Develop models to run on a high performance computer

References

Y. Gonthier. *Contact Dynamics Modelling for Robotic Task Simulation*. PhD thesis, University of Waterloo, 2007.

Y. Gonthier, J. McPhee, and C. Lange. On the implementation of Coulomb friction in a volumetric-based model for contact dynamics. In *Proceedings of ASME IDETC*, Las Vegas, Nevada, September 2007.