14. Principles of Kinematic Constraint

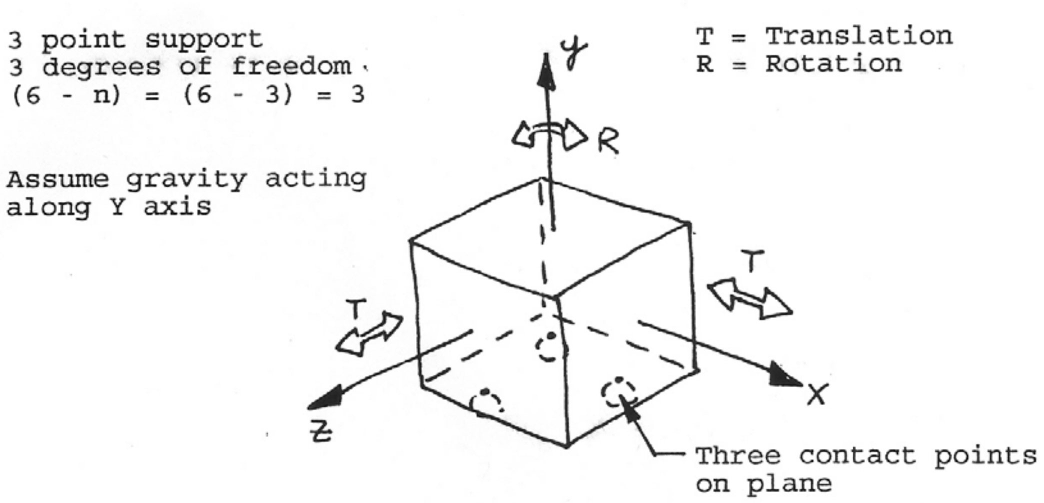
For holding a body (rigid thing) with the highest precision, we require:

- Full 6 DoF constraint
  - If 6 DoFs not fully constrained, then one is loose.

- No overconstraint
  - Any overconstraint can cause problems:
    - constraints can push against each other, resulting in stress and deformation.
    - constraints pushing against each other will “lurch” when forces exceed threshold

Kinematic constraint : All DoFs are constrained, and very strictly, none are overconstrained

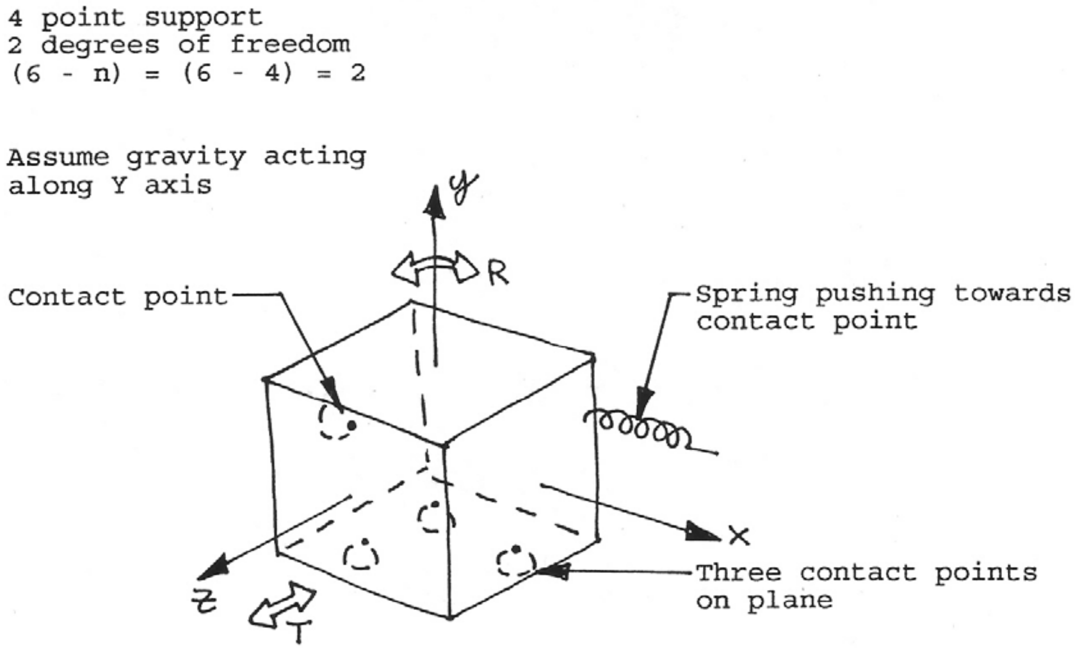
Semi-Kinematic : Slight overconstraint is allowed



What if you use 4 points in the plane?

What about 2 points?

What about 3 points in a line?



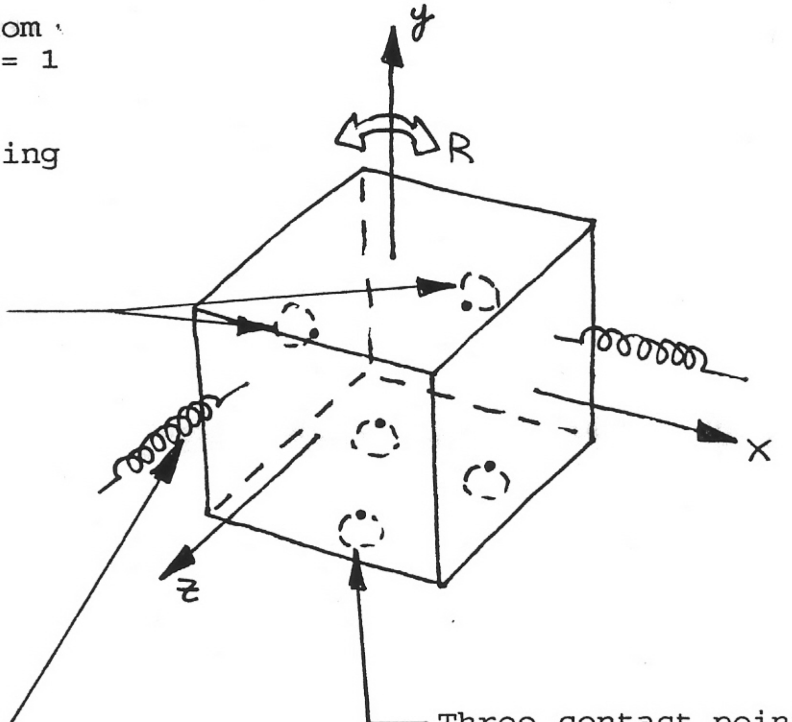
Balls provide position constraint.

Springs, gravity provide preload. NO CONSTRAINT!

(Vukobratovich p. 68)

5 point support
1 degrees of freedom
(6 - n) = (6 - 5) = 1

Assume gravity acting along Y axis



Two contact points

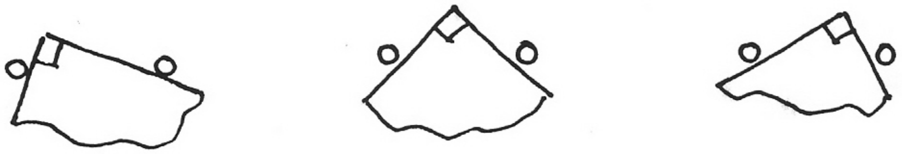
Springs pushing towards contact points

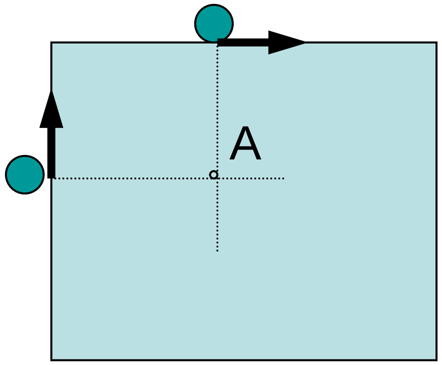
Three contact points on plane

One DoF left

Small motion : Rotation about point A

Shows indeterminacy of upper two points.





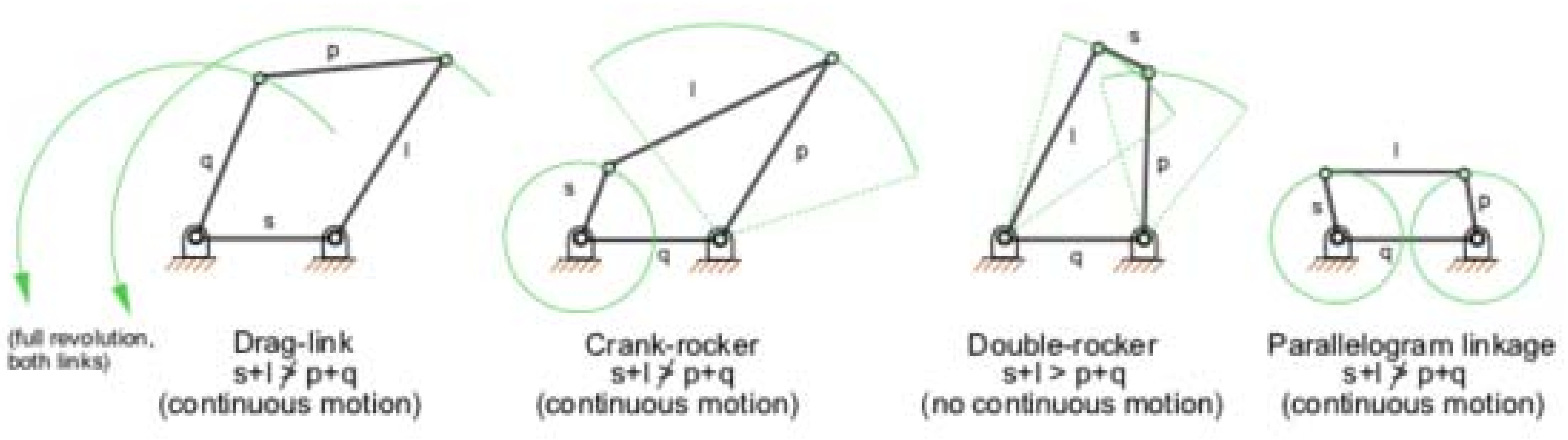
(Vukobratovich p. 69)

Instantaneous center of rotation

Same concept as four-bar linkage.

Instantaneous degree of freedom is rotation about a well defined point
- for small motions

For large motions, the geometry changes and the position of this instantaneous center of rotation moves.



(full revolution, both links)

Drag-link
s+l ≯ p+q
(continuous motion)

Crank-rocker
s+l ≯ p+q
(continuous motion)

Double-rocker
s+l > p+q
(no continuous motion)

Parallelogram linkage
s+l ≯ p+q
(continuous motion)

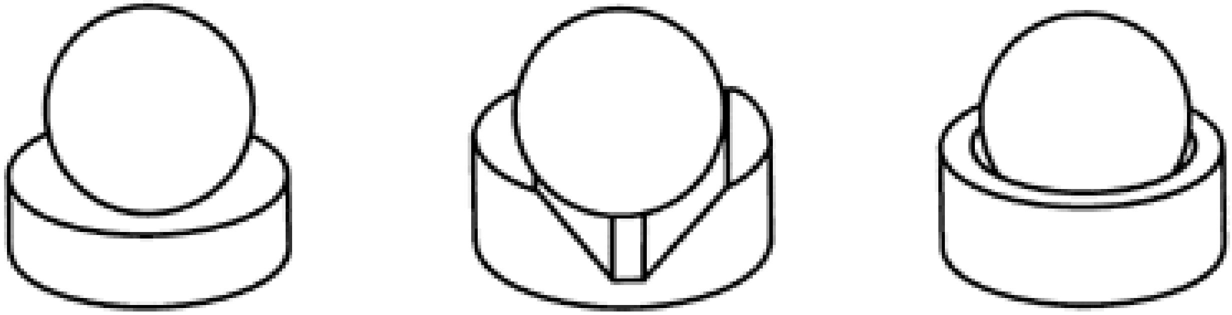
http://kmoddl.library.cornell.edu/resources.php?id=125

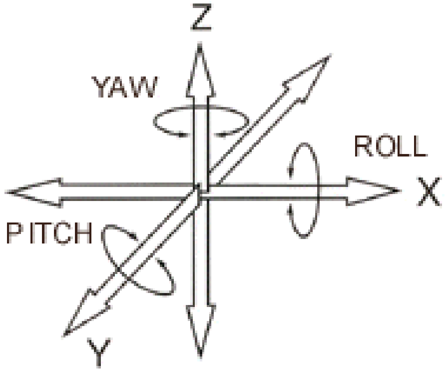
http://pergatory.mit.edu/2.007/lectures/2002/Lectures/Topic_04_Linkages.pdf

Use of balls

- Use symmetry of balls
- Material: Stainless steel, tungsten carbide, silicon nitride, diamond

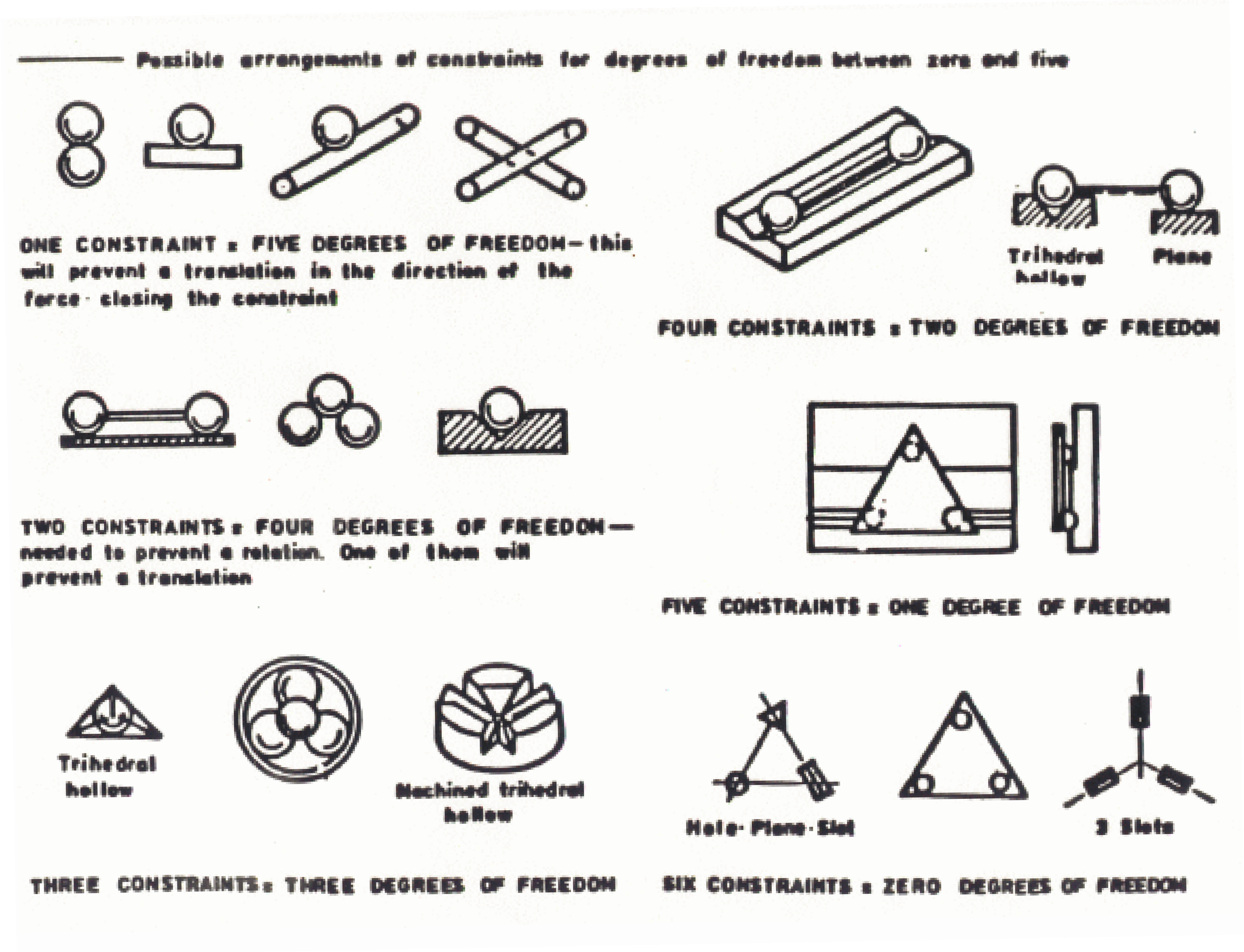
- Constrain position in 1, 2, or 3 DoF





- Always leaves rotation about 3 axes about center of curvature, *If the ball is smooth*

Possible arrangements of constraints for degrees of freedom between zero and five



ONE CONSTRAINT = FIVE DEGREES OF FREEDOM—this will prevent a translation in the direction of the force closing the constraint

TWO CONSTRAINTS = FOUR DEGREES OF FREEDOM—needed to prevent a rotation. One of them will prevent a translation

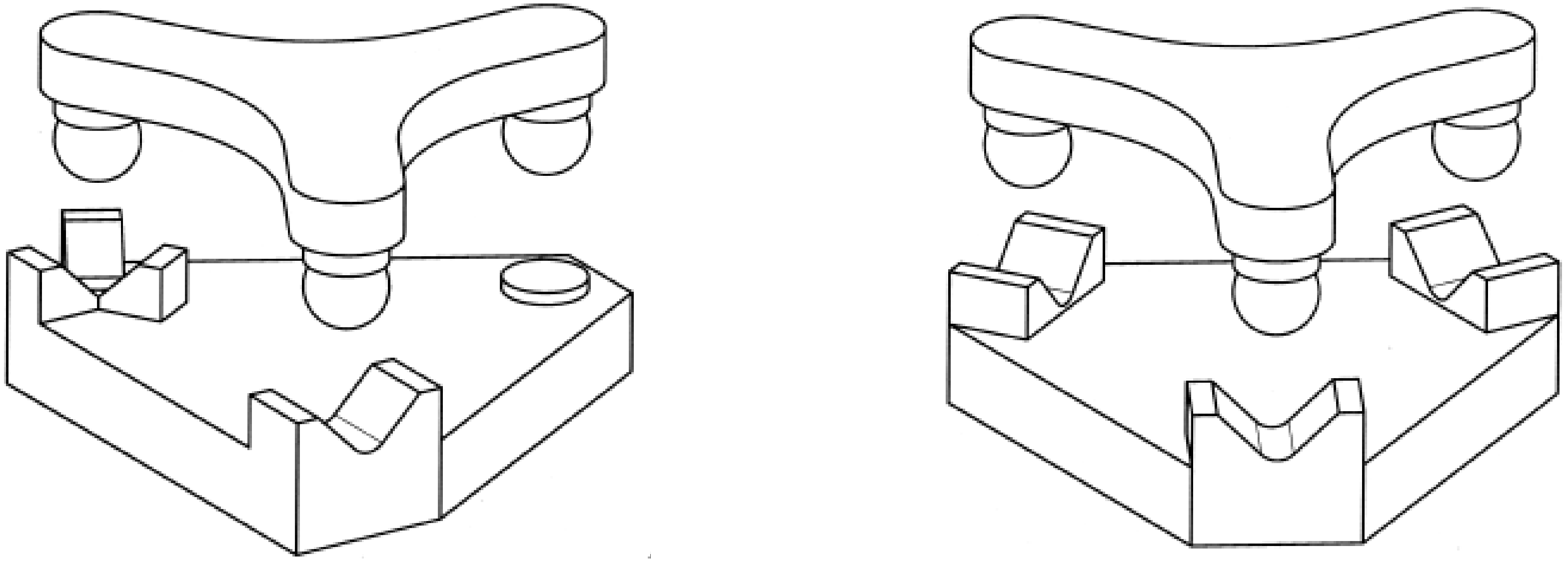
THREE CONSTRAINTS = THREE DEGREES OF FREEDOM

FOUR CONSTRAINTS = TWO DEGREES OF FREEDOM

FIVE CONSTRAINTS = ONE DEGREE OF FREEDOM

SIX CONSTRAINTS = ZERO DEGREES OF FREEDOM

Kinematic interface



(a)

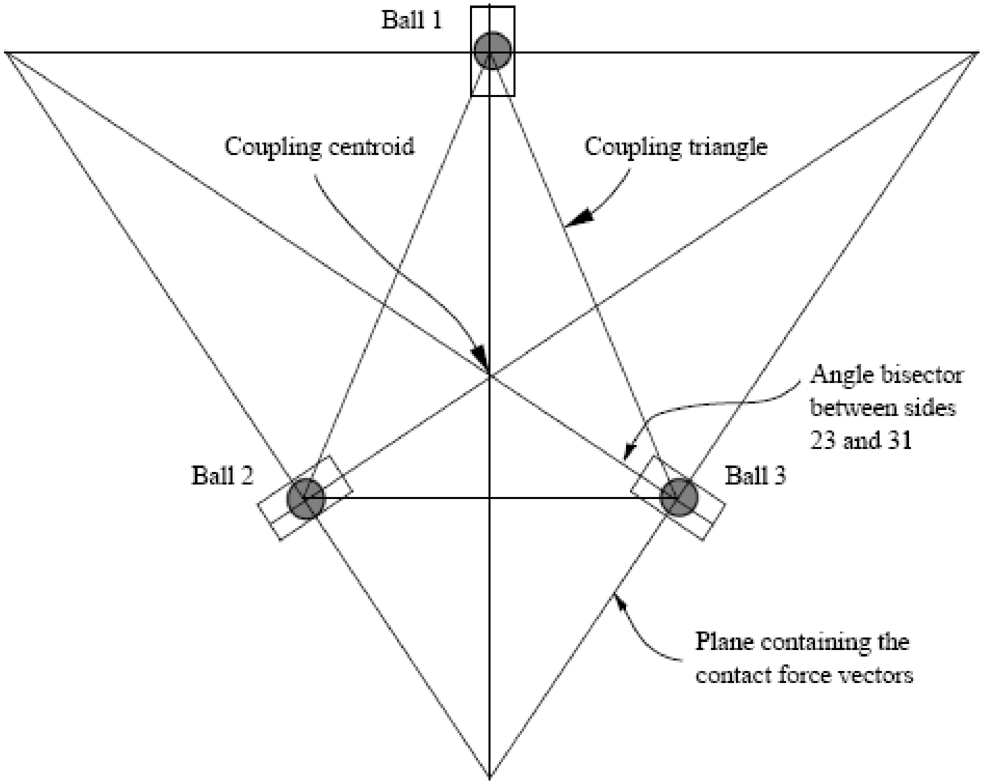
split Vee Block with
a large sphere

small spherical buttons
of a large spherical radius
and split Vee Block

(Hale and Slocum 2001)

3 V geometry

- **Ideally, the normals to the contact planes should bisect the coupling triangle's angles:**



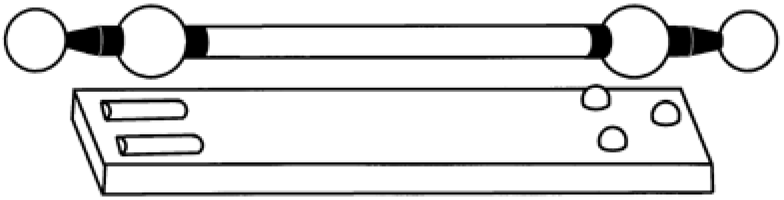
(Slocum 1994)

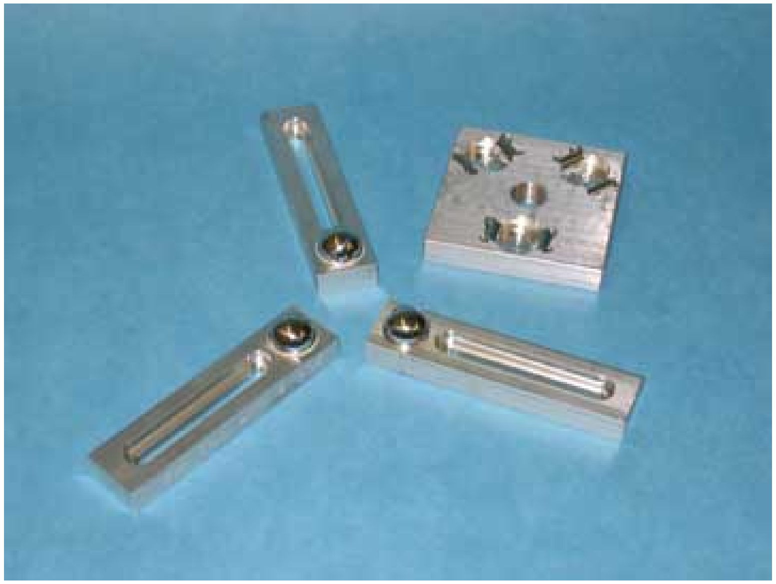
Kinematic hardware


Bal-tec

Kinematic Components

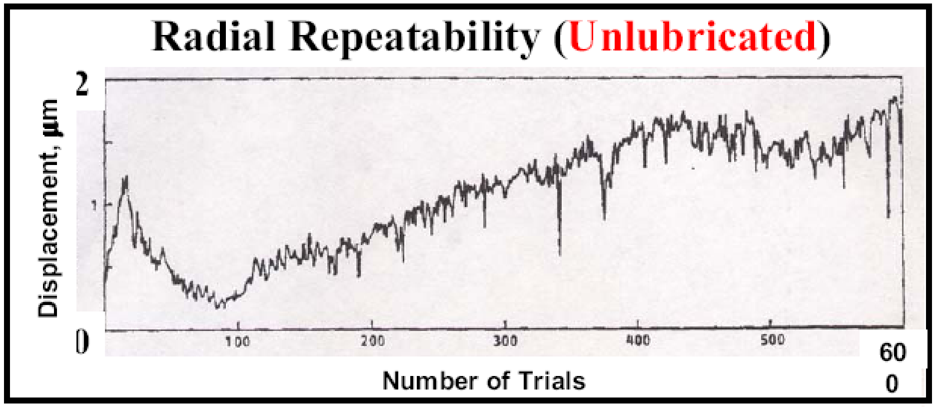
Catalog #105-A

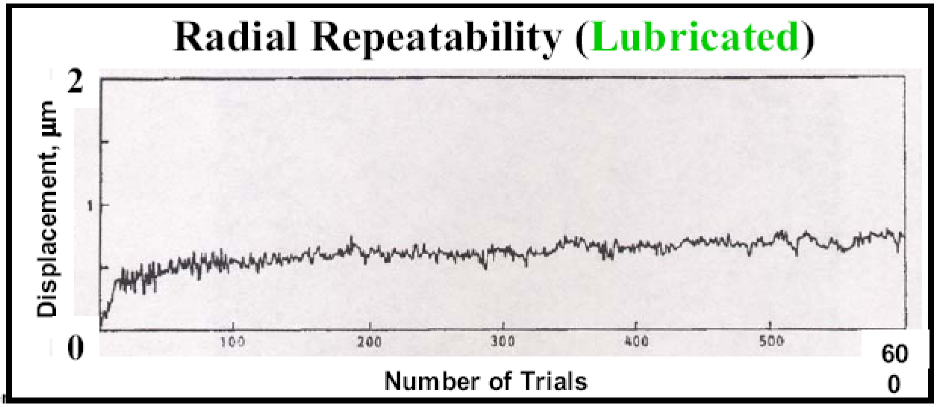




Kinematic location

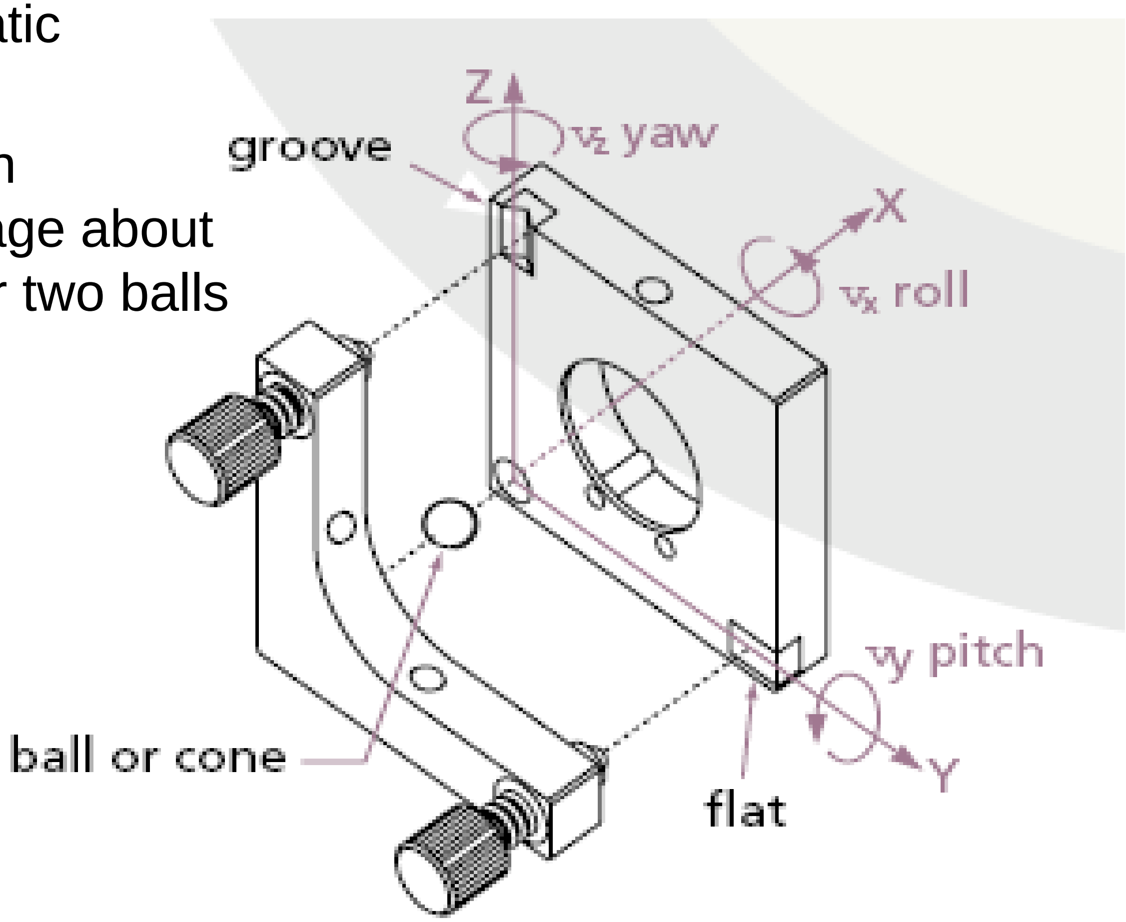
- Since the point contacts are well defined, the location is repeatable to sub-micron.
- Depends on friction, surface finish, loads.


Radial Repeatability (Unlubricated)


Radial Repeatability (Lubricated)

Application of kinematic constraint for precision motion

- For three balls fixed, kinematic constraint
- Move one ball at a time (with micrometer) to rotate the stage about the axis defined by the other two balls
- Very stable
- Smooth motion



(Not shown, springs that hold this together)

Application of kinematic concepts for motion control

5 DoFs constrained using kinematic principles

Remaining DoF is used for the motion

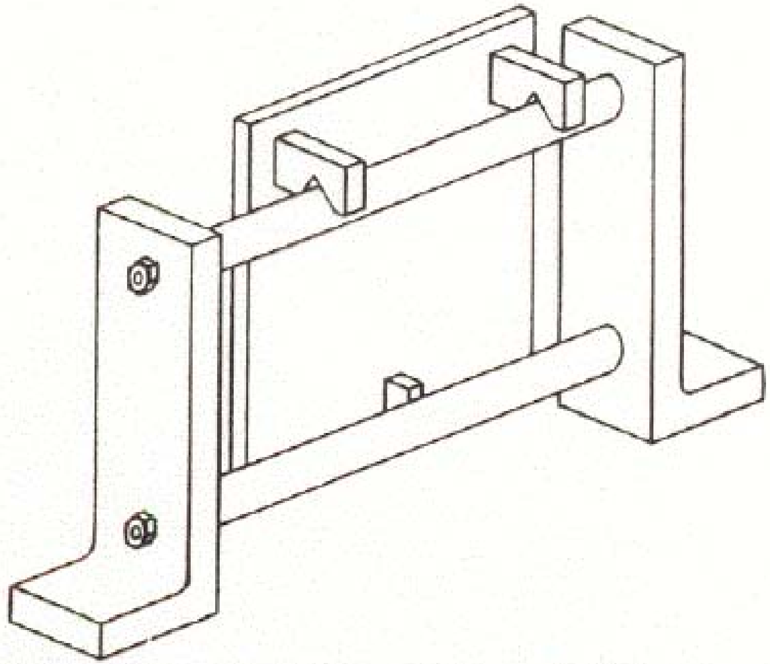
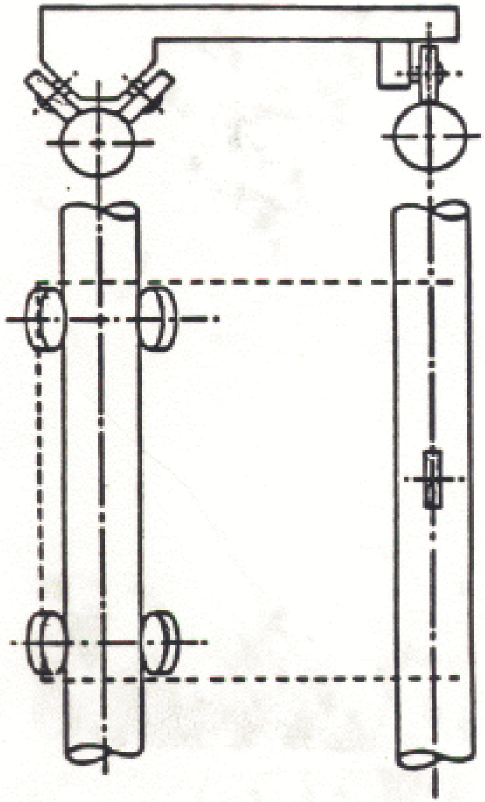
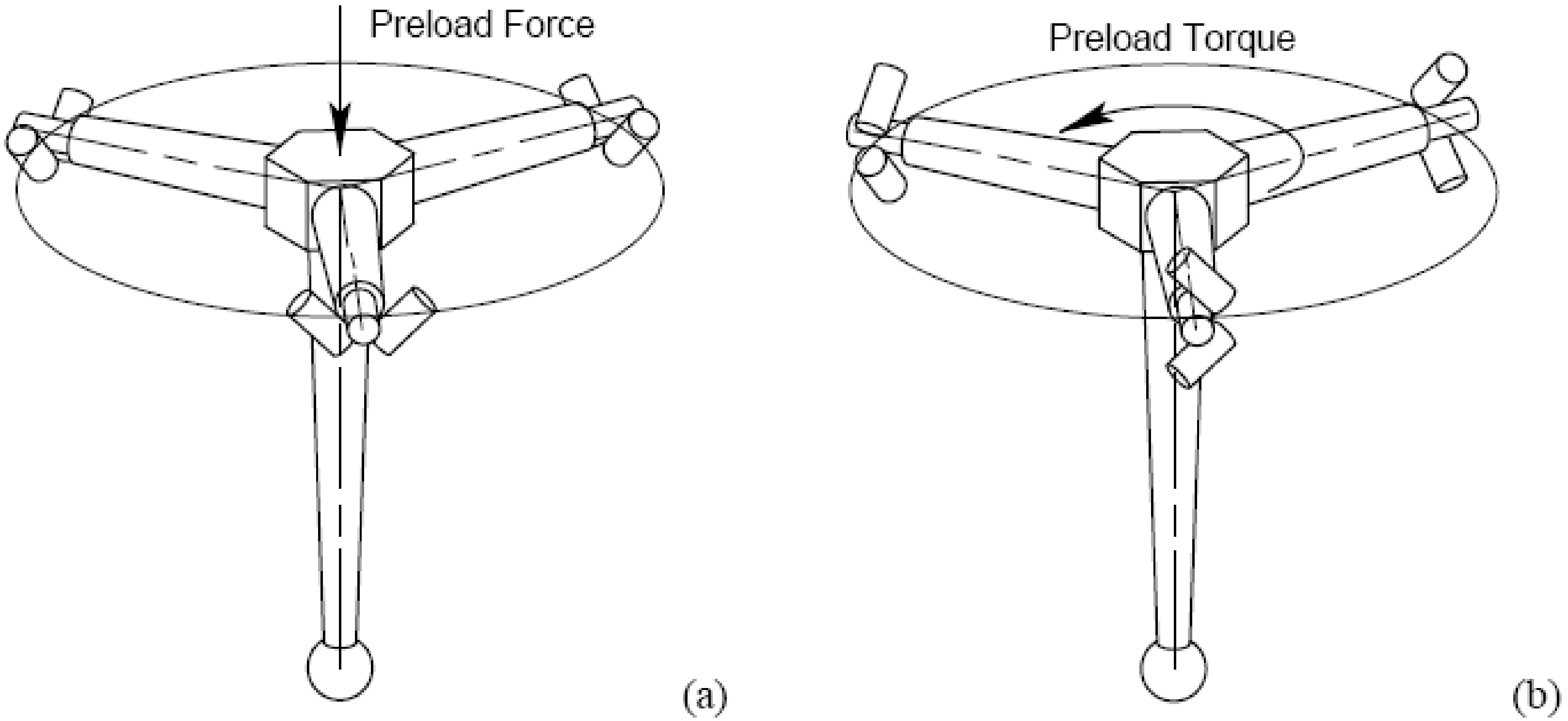


FIG. 6.2.—Kinematic design employing cylindrical surfaces as guides. Such surfaces can be accurately made.



Direction of V and preload



(a) (b)

Figure 6-7 In (a), the moment required to unseat one vee while pivoting about the other two vees is a factor of two less than the moment required to unseat two vees while pivoting about the third vee. In (b), a moment applied about any axis in the plane of the vees produces equal reaction at all vees.

Problems with point and line contact

Nominally, the contact area is **zero** for a point or line

Really, the contact area comes from deformations and depends on the geometry and material properties.

More force causes more deformation which increases the contact area.

Non-point contact = not purely kinematic

Stiffness = Force required for displacement is very low for the unloaded case. and very nonlinear. Preload is required.

Increased preloading makes stiffer, more stable interface in normal direction

But:

Stress = Force/Area is very high and can damage the materials

Tangential effects due to friction can be large

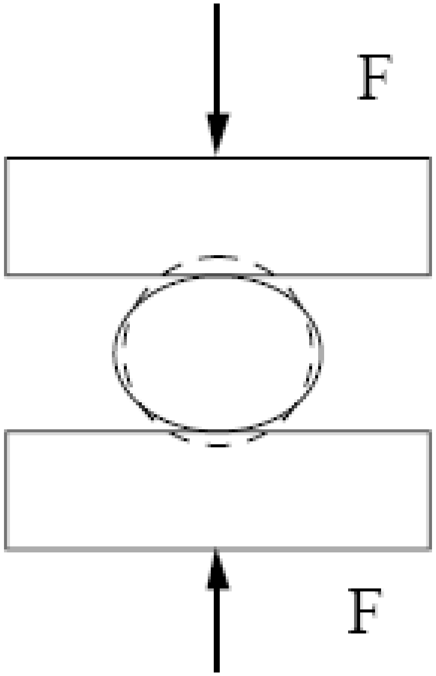
Hertz contact stresses are covered in Vukobratovish pp. 62-65.

Stiffness

$$\delta = \lambda \left(\frac{2F^2}{3R_e E_e^2} \right)^{1/3}$$

$$E_e = \frac{1}{\frac{1 - \eta_1^2}{E_1} + \frac{1 - \eta_2^2}{E_2}}$$

$$R_e = \frac{1}{\frac{1}{R1_{major}} + \frac{1}{R1_{minor}} + \frac{1}{R2_{major}} + \frac{1}{R2_{minor}}}$$

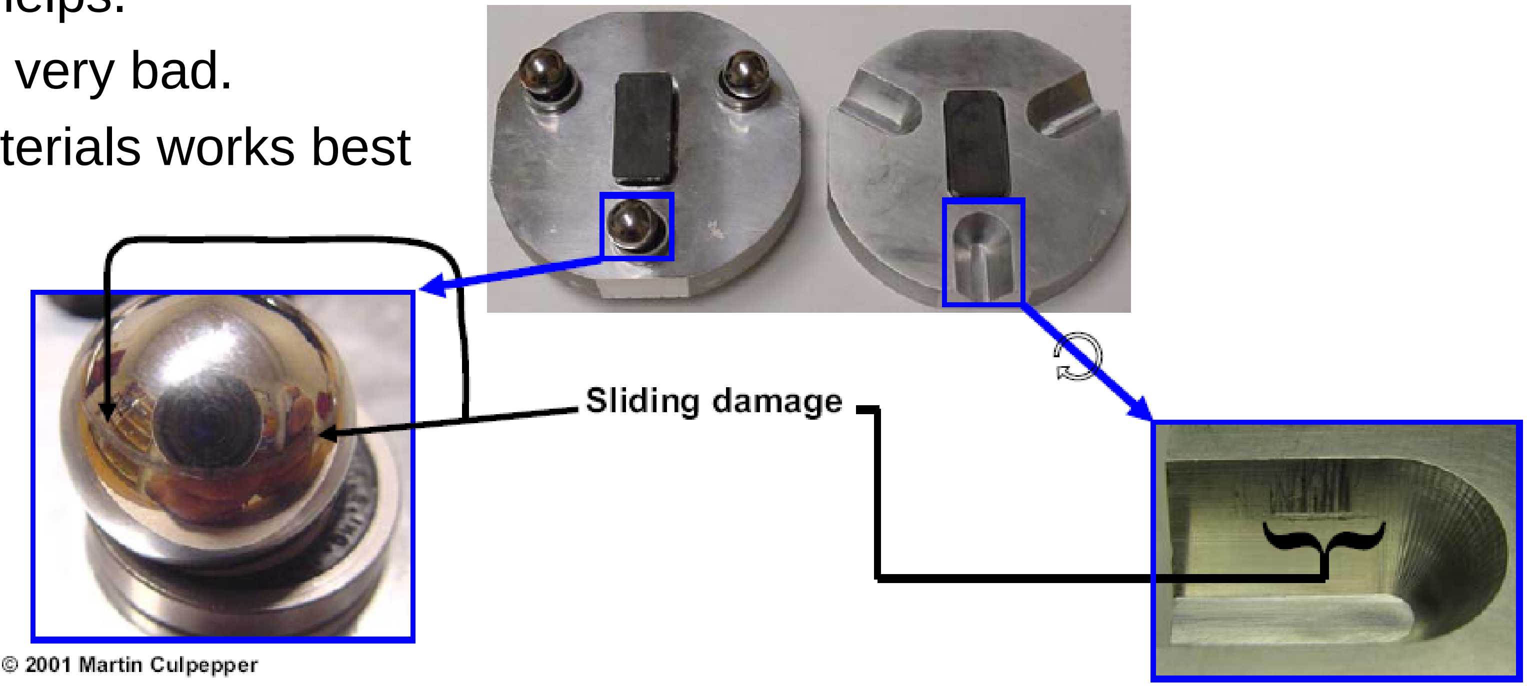


$$\Delta = 2\delta$$

(Slocum 1994)

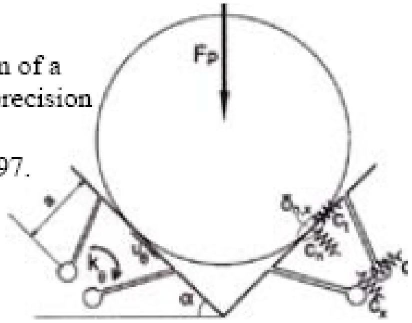
Effect of contact stress

- Contact stress can cause fretting of the surface
- Lubrication helps.
- Aluminum is very bad.
- Different materials works best



© 2001 Martin Culpepper

Picture from:
Schouten, et. al., "Design of a kinematic coupling for precision applications", Precision Engineering, vol. 20, 1997.



Ball in V-Groove with Elastic Hinges

Repeatability as function of geometry

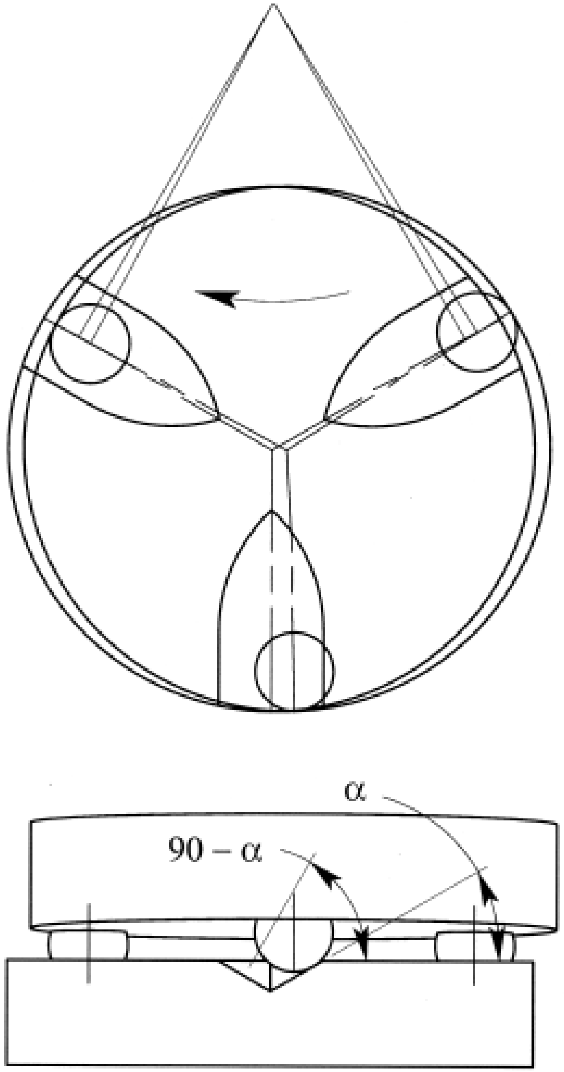


Fig. 5. The three-vee coupling slides on five constraints producing rotation about an instant center shown in the top view and also about an axis through the two seated balls.

Non-repeatability per ball/plane interface is

$$\rho \equiv \frac{f}{k} \approx \mu\left(\frac{2}{3R}\right)^{1/3}\left(\frac{P}{E}\right)^{2/3}$$

μ = friction coefficient
R = ball radius
P = load
E = Young’s modulus

For the system (mostly horizontal):

$$\rho \cong \frac{\mu P}{18k\ sin^2\alpha\ \cos\alpha}\left(2\sqrt{3} + \cos\alpha + \sin 2\alpha\right)$$

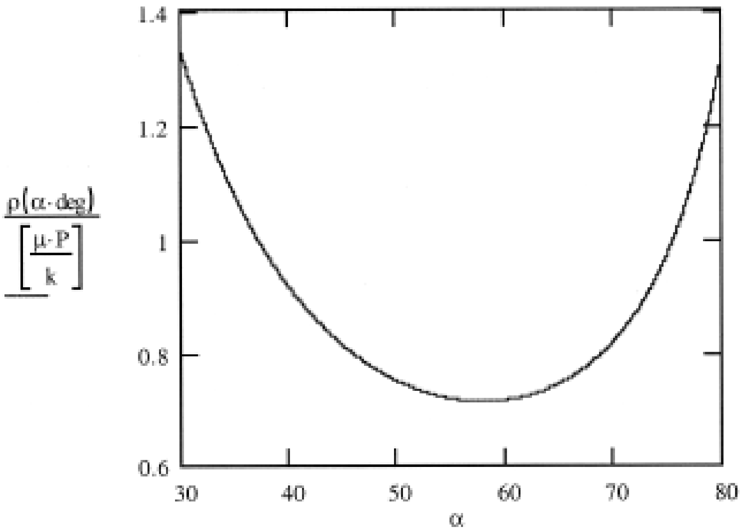


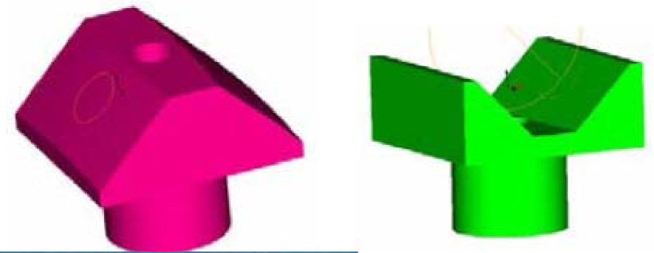
Fig. 6. The effect of the vee angle α on the repeatability of the symmetric three-vee coupling has a minimum of 0.71 at 58°.

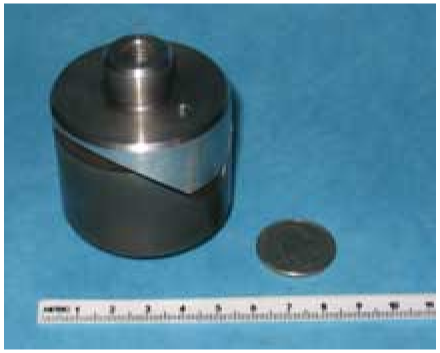
Use geometry to reduce contact stress

“Canoe ball”

1 meter ROC

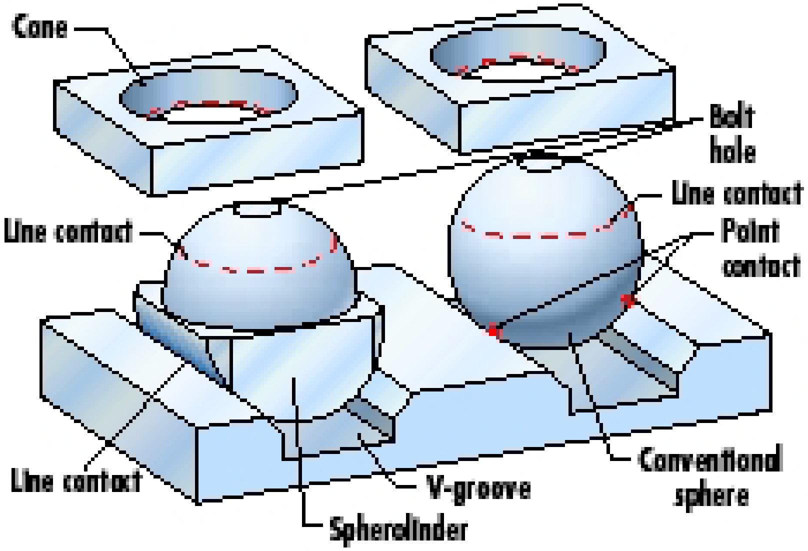
(Baltek)





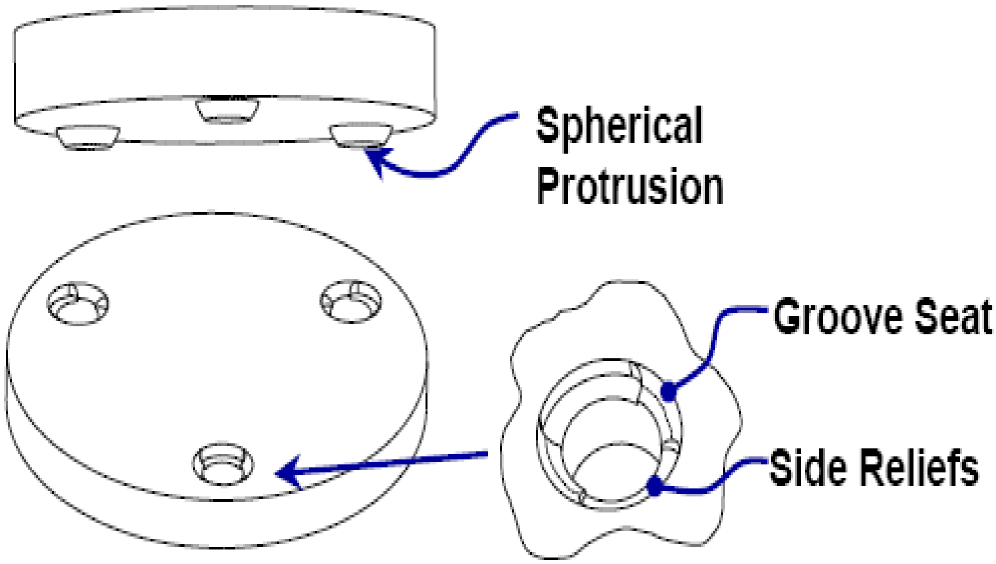
“Spherolinder”

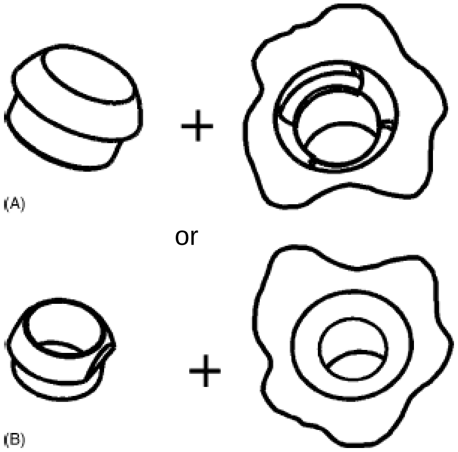
G2 Engineering



Semi-kinematic design

L. Hale US Patent #6,065,898





Cylinders in V's

- Easy to make to high accuracy
- Leaves axial motion, clocking rotation unconstrained

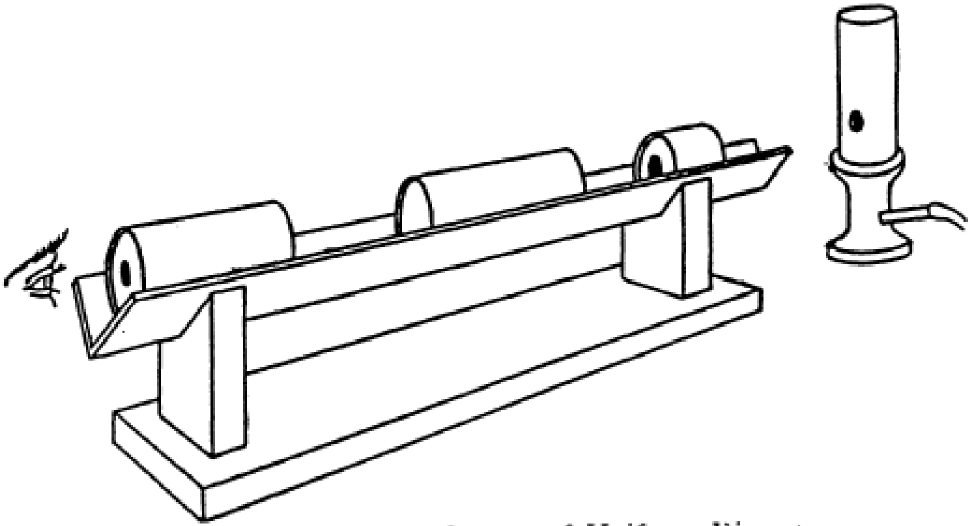
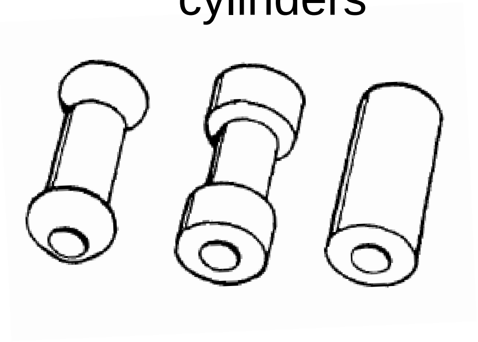


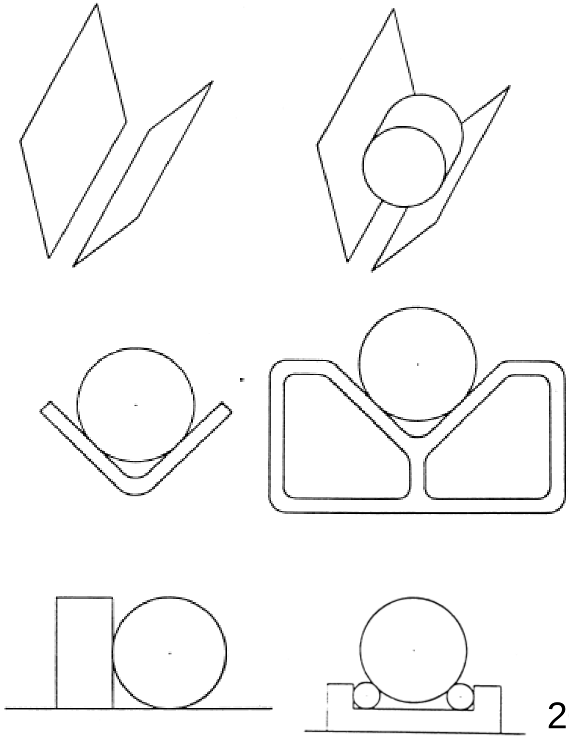
FIG. 59.—V Bench for Lenses of Uniform Diameter.

Fig 35 - From *Treatise on Practical Light*, 1911

cylinders



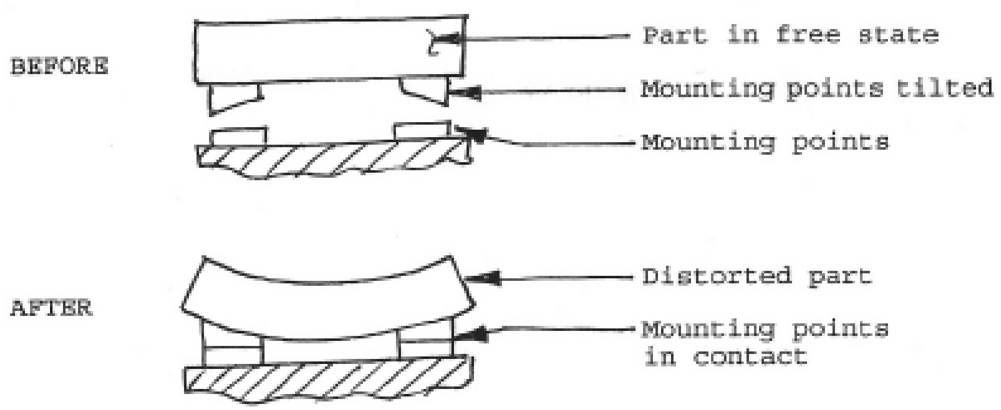
V's



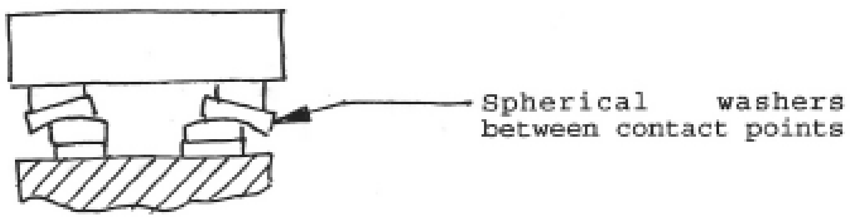
"Cylinders in Vs—An Optomechanical Methodology," Douglas S. Goodman, SPIE Proceedings 3132 *Optomechanical Design and Precision Instruments*, Santa Diego, CA, July, 1997

"More Cylinders in Vs," Douglas S. Goodman, SPIE Proceedings 4198, *Optomechanical Engineering*, Boston, MA, November, 2000

- A major problem with kinematic design is high stress in contact areas. Hertz contact stress theory is used to evaluate this problem.
- If stress is too high, use kinematic principles but replace point contacts with small area contacts. This is known as semi-kinematic design.
- A potential problem with semi-kinematic design is distortion of the part due to non-coplanarity of the mounting points.



- This problem is alleviated by making points very coplanar by introducing rotary compliance in the mounting points.



- Assembly procedures for semi-kinematic design are usually critical if part distortion is to be avoided.

(Vukobratovich p. 76)

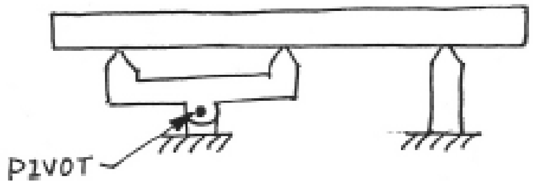
- Kinematic mounted parts may have excessive self-weight induced deflection between contact points. This requires additional support which nullifies kinematic design.

- One solution to the multi-point problem is a whiffle tree. This is a cascaded system of support where each level of support is kinematic.

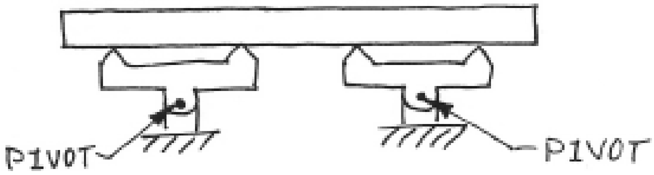
- Consider a simple beam:

2 point support

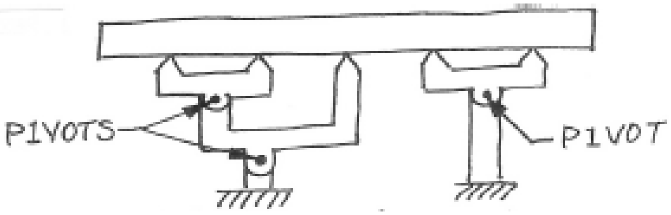
3 point support



4 point support



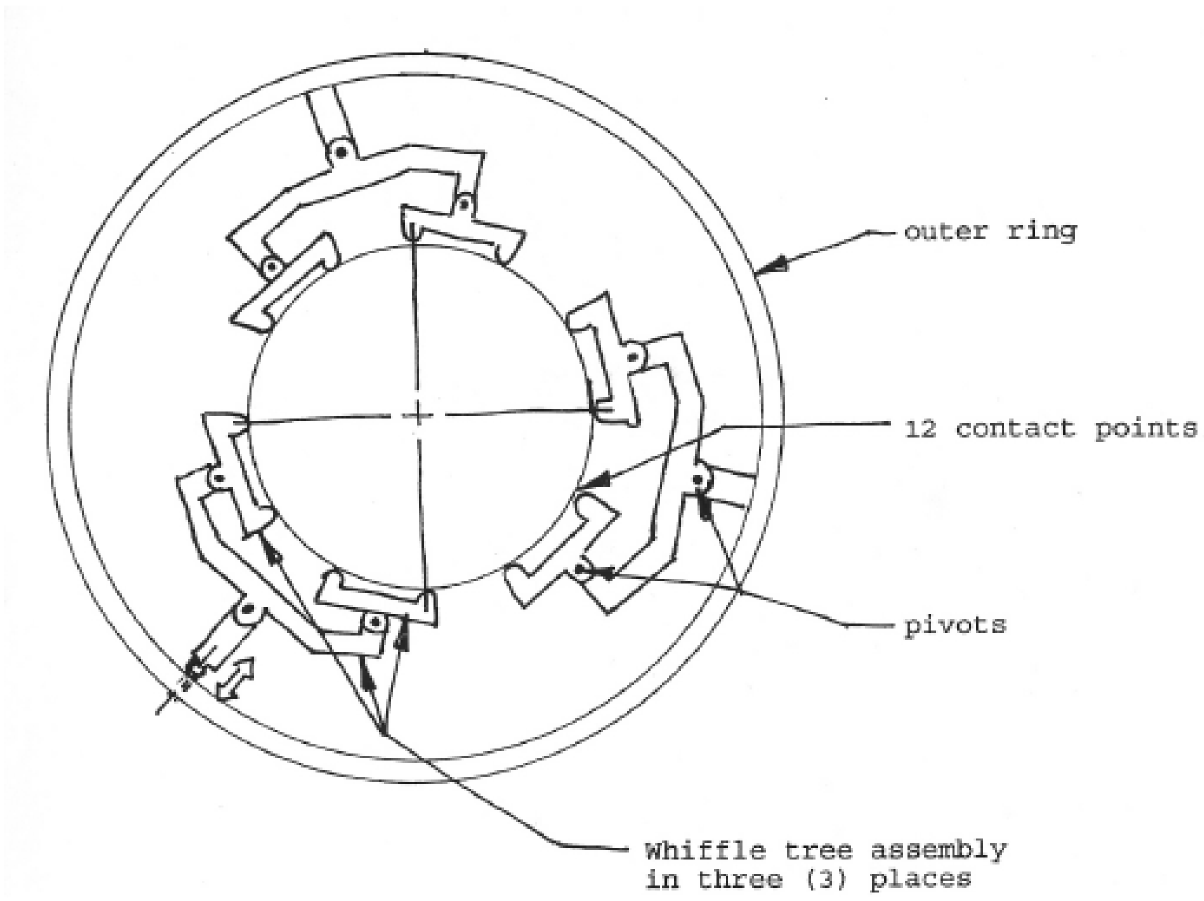
5 point support



NOTE: Pivots insure equal loads on each support.

(Vukobratovich p. 78)

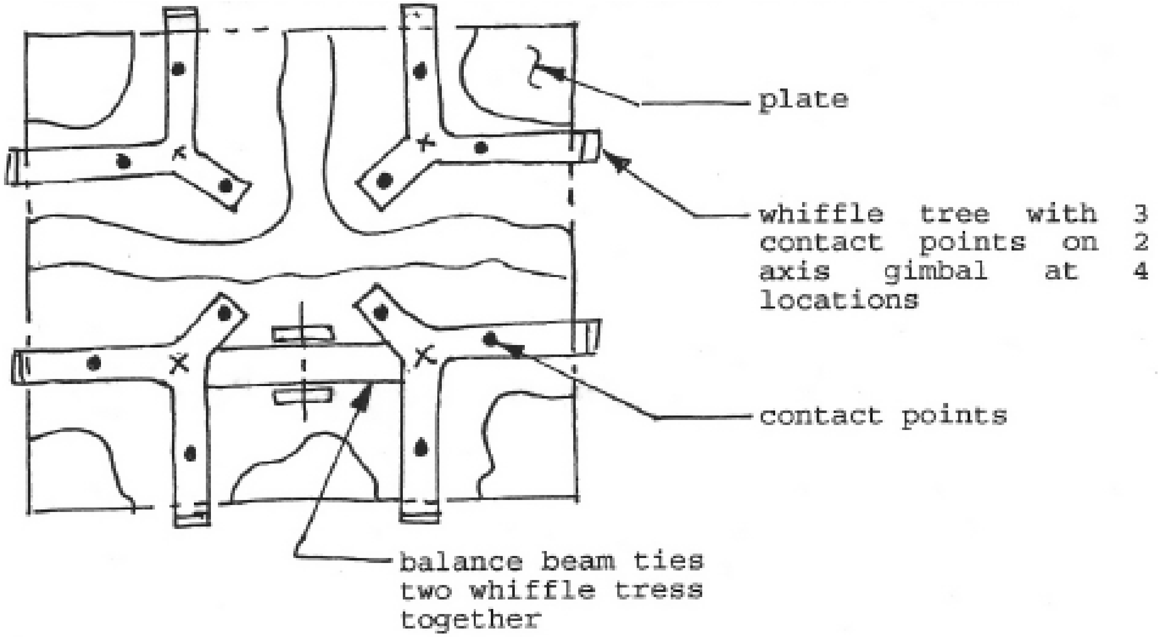
- The same approach can be used to support a disk around its edge.

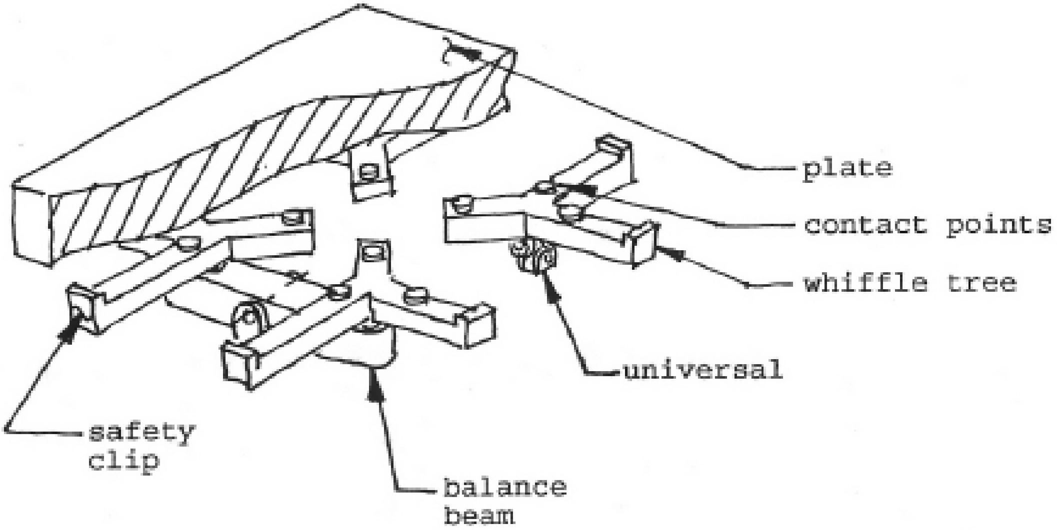


- This approach gives an even distribution of forces yet preserves a three (3) point kinematic location system.

(Vukobratovich p. 79)

- The same approach also “floats” plates on whiffle trees.





(Vukobratovich p. 80)