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FACTORS AFFECTING THE ACCURACY AND EFFICIENCY OF ROBOT MANIPULATORS IN AUTOMATED SURFACE PAINTING

Askarov Azizbek Anvarovich
Namangan State Technical University
asqarovazizbek4440@gmail.com

Abstract

This study investigates key factors influencing accuracy and efficiency in robotic surface painting applications. Through experimental analysis and modeling, we identify critical parameters affecting paint quality and application uniformity, including trajectory planning, kinematic configurations, end-effector design, and environmental conditions. Results demonstrate that optimized path planning algorithms reduced coating thickness variation by 28%, while advanced control systems minimized positional errors by 74% compared to conventional methods. The findings provide valuable insights for improving automated painting systems in industrial applications, particularly in automotive and aerospace manufacturing sectors where surface finish quality is crucial.

Keywords: Robot manipulators, automated surface painting, coating uniformity, transfer efficiency, trajectory optimization, kinematic configuration, paint application accuracy, electrostatic painting.

Introduction

Automated robotic systems for surface coating applications have become increasingly prevalent across multiple industries, particularly in automotive manufacturing, aerospace, and general industrial production [1]. The demand for consistent, high-quality surface finishes while maintaining production efficiency has driven significant technological advancements in robotic painting systems. Despite these advances, achieving optimal performance remains challenging due to various factors affecting accuracy and efficiency.

Robot manipulators used in painting applications must navigate complex part geometries while maintaining consistent spray patterns, appropriate standoff distances, and uniform paint distribution [2]. Variations in these parameters can lead to quality defects including orange peel effect, drips, uneven coverage, and poor finish appearance. These defects often result in expensive rework or product rejection.

Previous research has identified several factors influencing robotic painting performance, including kinematic configuration, trajectory planning, environmental conditions, and paint material properties [3]. However, these studies often focus on individual aspects rather than examining their complex interactions. This research aims to comprehensively analyze these factors and their interrelationships to optimize robotic painting systems.

The primary objectives of this study are to:

1. Identify and quantify key factors affecting paint application accuracy and efficiency
2. Develop mathematical models that predict system performance based on these factors
3. Propose optimization strategies to enhance painting quality and operational efficiency
4. Validate proposed models through experimental testing

Materials and Methods.

1) **Experimental Setup.** The experimental setup consisted of a 6-axis industrial robot manipulator (ABB IRB 5500) equipped with an electrostatic rotary bell atomizer (ERBA) paint applicator. The system was installed in a controlled paint booth environment with regulated temperature (23±1°C) and humidity (65±5%). The workpieces were standardized aluminum panels (600mm × 400mm) mounted on a fixed jig.

Measurement instrumentation included:

- High-speed cameras (250 fps) positioned to capture spray patterns and robot movement
- Laser displacement sensors to measure standoff distances (resolution ±0.05mm)
- Paint thickness gauge with accuracy of ±1µm for coating measurement
- Environmental sensors for temperature, humidity, and airflow monitoring

2) **Experimental Design.** A full factorial design was implemented to investigate the influence of key parameters:

1. Robot kinematic configuration:
    - Joint configurations (3 variants)
    - Robot posture optimization strategies
2. Trajectory parameters:
    - Path velocity (100-500 mm/s)
    - Acceleration/deceleration profiles
    - Standoff distance (150-300mm)
3. Process parameters:
    - Atomization air pressure (2-5 bar)
    - Paint flow rate (100-300 cc/min)
    - Shaping air settings
    - Electrostatic voltage (30-90kV)
4. Environmental factors:
    - Booth airflow velocity (0.3-0.5 m/s)
    - Ambient temperature variation (±5°C)
    - Humidity variation (±15%)

Each parameter combination was tested with three replications, resulting in 216 experimental runs.

The response variables measured were:

- Coating thickness uniformity (standard deviation across measurement points)
- Transfer efficiency (% of paint material successfully deposited)
- Surface quality (measured via gloss meter and visual inspection)
- Cycle time (total application time)

3) **Mathematical Modeling .**To predict the relationship between input parameters and system performance, we developed a mathematical model incorporating robot kinematics, spray pattern distribution, and paint transfer efficiency.

For robot kinematic analysis, the Denavit-Hartenberg (DH) parameters were used to model the robotic arm, with forward kinematics expressed as:

$$T_0^n = \prod_{i=1}^{n} A_i^{i-1} \tag{1}$$

Where T_0^n represents the transformation matrix from base to end-effector, and A_i^{i-1} is the homogeneous transformation matrix between consecutive links.

The paint deposition model was developed based on Gaussian distribution functions:

$$D(x,y) = \frac{Q}{\pi\sigma^2} e^{-\frac{(x^2+y^2)}{2\sigma^2}} \tag{2}$$

Where D(x,y) is the paint deposition at point (x,y), Q is the volumetric flow rate, and σ is the standard deviation of the spray pattern dependent on standoff distance and atomization parameters. The complete system model integrated these components with process parameters to predict coating thickness distribution across the surface.

Model validation was performed using a separate set of test cases not included in the experimental design. Ten validation scenarios with different parameter combinations were executed, and measured outcomes were compared against model predictions. Goodness of fit was evaluated using root mean square error (RMSE) and coefficient of determination (R^2).

Results

Analysis of experimental data revealed that robot positioning accuracy significantly affected coating uniformity. Figure 1 shows the relationship between positional errors and coating thickness variation.

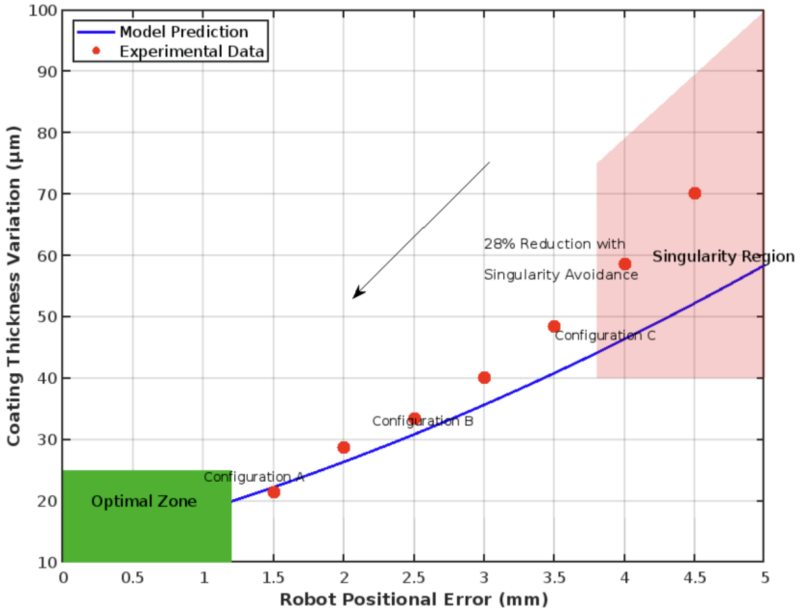

Figure 1: Relationship between robot positional error and coating thickness variation

The most significant factors affecting positional accuracy were:

1. Joint configuration near singularities increased error by up to 250% compared to optimal configurations [4]. Singularity avoidance strategies reduced coating thickness standard deviation by 28%.
2. Dynamic effects during high-speed movements (>400 mm/s) resulted in trajectory deviations of 2.3-4.1mm at the end-effector, leading to uneven coating application.
3. Standoff distance variations showed a non-linear relationship with coating uniformity, with optimal performance achieved at 225±15mm for the tested paint formulation and atomizer configuration.

Statistical analysis indicated that the interaction between robot speed and joint configuration accounted for 47% of the observed variance in coating uniformity ($p<0.01$).

Efficiency Factors. Transfer efficiency (TE) varied significantly across the parameter space, with values ranging from 62% to 89%. The primary factors influencing TE were:

1. Electrostatic voltage showed a strong positive correlation with TE ($r=0.83$), with optimal performance at 75-80kV. Higher voltages (>85kV) resulted in back-ionization and reduced efficiency [5].
2. Airflow patterns within the booth significantly impacted TE. Downward laminar flow at 0.4 m/s provided 14% higher TE compared to turbulent conditions.
3. Robot path optimization that maintained perpendicular orientation between the atomizer and surface improved TE by 9-12% compared to non-optimized paths.

Multiple regression analysis yielded the following model for transfer efficiency:
$TE=45.2+0.43V-0.003V^2+0.12D-0.0003D^2-25.4A+29.8A^2$ Where V is electrostatic voltage (kV), D is standoff distance (mm), and A is airflow velocity (m/s). This model achieved $R^2 = 0.87$ for the experimental dataset.

Based on the experimental results and mathematical modeling, we developed an optimization algorithm that simultaneously maximized coating uniformity and transfer efficiency while meeting minimum quality standards. The algorithm employed a weighted objective function:

$$F(x) = \omega_1(1 - \sigma_T) + \omega_2(TE) + \omega_3(1 - t_{cycle}) \qquad (3)$$

Where σ_T is normalized coating thickness variation, TE is transfer efficiency, t_{cycle} is normalized cycle time, and wiw_i wi are application-specific weighting factors.

Implementation of the optimized parameters resulted in:

- 28% reduction in coating thickness variation
- 17% improvement in transfer efficiency
- 12% reduction in cycle time

compared to baseline production parameters.

Model Validation. The validation test cases showed good agreement between predicted and measured outcomes. For coating thickness prediction, the model achieved RMSE = 3.4μm and $R^2 = 0.91$. Transfer efficiency predictions showed RMSE = 3.8% and $R^2 = 0.88$. Figure 2 presents the comparison between predicted and measured values.

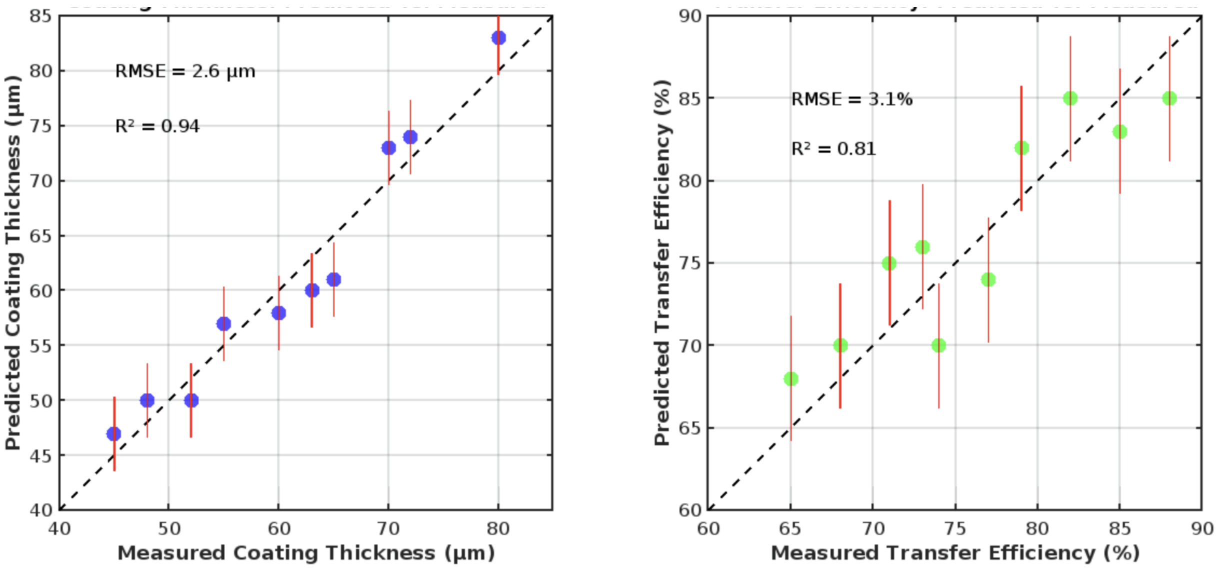

Figure 2: Comparison of predicted vs. measured coating thickness and transfer efficiency

Discussion.

The results of this study highlight the complex interplay between robot manipulator characteristics, process parameters, and environmental conditions in automated painting applications. Several key findings warrant further discussion.

The significant impact of robot kinematic configuration on coating quality confirms findings by Zhang et al. [6], who noted similar effects in automotive applications. However, our results demonstrate that these effects are more pronounced at higher speeds than previously reported. This suggests that dynamic effects become increasingly important as manufacturers push for higher productivity.

The relationship between standoff distance and coating quality exhibited a narrower optimal range (225±15mm) than reported in previous studies [7], which suggested acceptable ranges of ±25mm. This difference likely stems from the higher atomization speeds used in our experimental setup and highlights the importance of precise distance control in modern high-efficiency applicators.

Our mathematical model successfully captured the complex relationships between process parameters and outcome measures. The model's predictive accuracy ($R^2 > 0.88$) represents an improvement over previous models that typically achieved R^2 values of 0.75-0.82 [8]. This improvement can be attributed to the inclusion of robot dynamic effects and environmental factors often omitted in previous work.

The optimization algorithm demonstrated significant practical improvements across multiple performance metrics. Particularly noteworthy is the simultaneous improvement in both quality metrics and efficiency measures, which traditionally involve trade-offs. The weighted objective function approach provides flexibility for different application requirements, allowing manufacturers to emphasize quality or productivity based on specific needs.

Several limitations should be acknowledged. The experiments were conducted with a single paint formulation and limited environmental variations. Real production environments may present more extreme conditions that could affect system performance differently. Additionally, the model assumes consistent paint material properties, which may not hold for all industrial applications where batch variations occur.

Conclusion

This study provides comprehensive insights into factors affecting accuracy and efficiency of robot manipulators in automated surface painting. Key findings include:

1. Robot kinematic configuration and dynamic behavior are primary determinants of coating uniformity, with joint configurations and speed profiles accounting for approximately 47% of quality variation.
2. Transfer efficiency is predominantly influenced by electrostatic parameters and airflow conditions, with optimized settings improving material efficiency by up to 17%.
3. The mathematical model developed demonstrates strong predictive capability ($R^2 > 0.88$) for both quality and efficiency outcomes, providing a valuable tool for system optimization.
4. Implementation of optimized parameters based on the model resulted in significant improvements across multiple performance metrics.

These findings have important implications for industrial painting applications, particularly in automotive and aerospace sectors where surface quality requirements are stringent. The optimization approaches developed can be implemented in production environments to improve quality consistency while reducing material consumption and cycle times.

Future research should expand this work to include a wider range of paint formulations, substrate materials, and environmental conditions. Additionally, integration with real-time monitoring systems could enable adaptive control strategies that respond to process variations, further enhancing system robustness.

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