Improving the Efficiency of Excavators Increasing the Efficiency of Temporary Ditch Excavator

Djaksimuratov Karamatdin Mustapaevich	Candidate of Natural Sciences, Nukus Mining Institute
Jumabayeva Guljahon Jaqsilikovna	Nukus Mining Institute "Natural and general professional sciences" intern teacher
Maulenov Nurlibek Axmet o'g'li	Student of Nukus Mining Institute
Rametullayeva Mehriban Po'latbek qizi	Student of Nukus Mining Institute

ABSTRACT

The article notes that two straight – disc drives are installed in front of the channel excavator in order to improve the irrigation, thus reducing the quality of the channel excavation. During the excavation, due to partial disintegration of the soil layer due to rotational movement of the discs, the slope of the ditch is maintained at the required level and interrupted the problem of maintaining the uniformity of the ditch sidewall. n recent years, some unmanned operation systems for the hydraulic excavator are required and some systems arealready developed. However, it is difficult to realize effective operation utilizing such systems, because the operator cannot sense ground condition. The skillful operator adaptive their operation to the excavating environment based on the experience, and realizing the efficient excavating. In this paper, we described the experiment for extracting operator's skill for controlling unmanned hydraulic excavator. We compare the operation of skillful with non-skillful operator and discuss the result for the modeling of operator's skill. From these results, we have revealed that skillful operator realizes unified trajectories of the bucket with quick moving and this causes the efficient performance.

Keywords: The greatest length, The smallest length, Maximum water consumption, Minimum water consumption, КОП-500А, КЗУ-0,5, КПУ-2000А, КБН-0,35, КЗУ-03,, temporary, longitudinal, cross. hydraulic excavator, autonomous control, operation skill, skill extraction.

In generally, it is required to excavate the ground by the construction machine such as the hydraulic excavator at the construction sites. In most of such construction sites, there would be bad environmental conditions because muddy surface of the ground, in full of exhaust tunnel and ambient noise, and these surrounding environments would break and fall. Therefore, there is possibility that the accident occurs involving the operator(Fig.1), and the unmanned excavator system is required. In recent years, the teleoperation systems has been developed and some of them are in practical use. In these teleoperation systems, the operator usually maneuvers the excavator by watching the work site directly from the operation site, or using image transmitted from the equipped cameras on the work site. In these systems, the operator cannot sense ground condition, soil property,

reaction force and relative position from the machine and the ground. Therefore the work efficiency by using these teleoperation systems decreases comparing to a direct control by human operator. On the other hands, there is an approach to realize the unmanned excavator operation based on the autonomous machine control system. For realizing the autonomous excavator system, it is necessary to plan the excavating trajectories using its kinematic model and operation model including environmental dynamics. However, actually, it is difficult to make its model and plan the excavating trajectories because of various considerable parameters such as friction coefficient of the soil, slip ratio and other ground conditions.

Fig.1 Excavator work under bad environment

Besides, it is thought that the skillful operator adaptive their operation to the excavating environment based on their empirical knowledge, and realizing the efficient excavating. In this study, we are developing an autonomous excavator control system with efficient operation function based on analyzed skills of operation by the skillful operator. In our previous works, we have developed the on-board measurement system for the motion of the excavator and operation input. Furthermore, excavation work had been experimented and operation data is collected.In this paper, we try to analyze the difference of the operation skills between skillful operators and non-skillful operators by comparing their bucket trajectories on the same working environment. Nowadays futher improvement of irrigated lands, wide spreading of intensive methods of agricultural production, first of oll, water and resourse-saving modern technologies is one of the fields which are well paid attention in The Republic of Uzbekistan. In this regard, the use of water-saving modern technologies and maintenance of irrigation networks is always in technically good condition, and creating and the use of

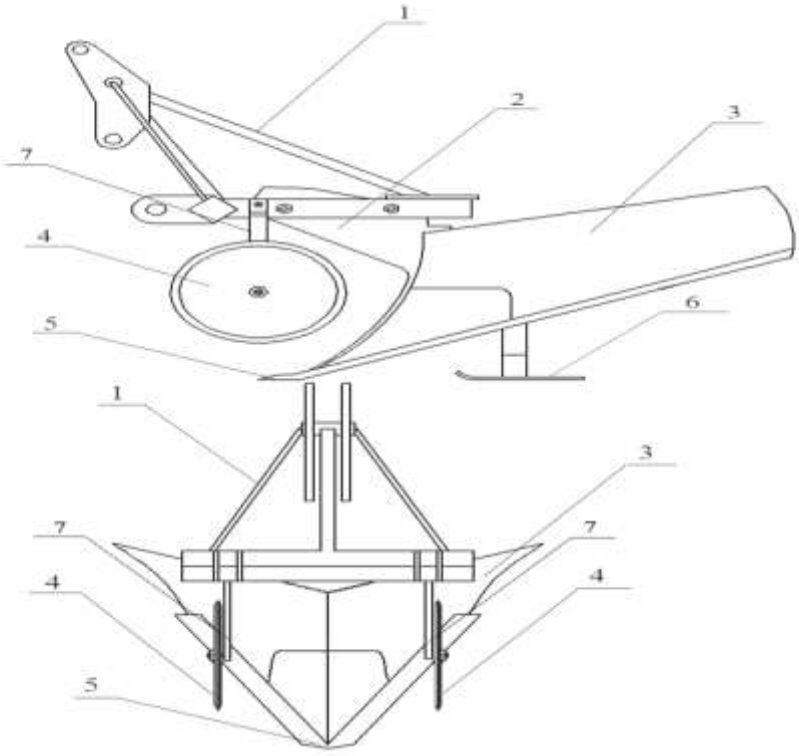
energy-saving modern technologies are very important. As we know, temporary irrigation networks are used for irrigating of crops on the surface of the ground. Temporary irrigation networks are dug at the beginning of the irrigation season and leveled after the end of the irrigation season. Temporary irrigation networks include temporary irrigation ditches, beams and irrigation furrows. The recommended moderate rates for temporary irrigation networks are shown in Table 1. (H.T. Лактаев).

1-table

The parametres of an arrow ditch *(The information of N.T.Laktaev)*

Parametres of a temporary ditch	Layout scheme	
	longitudinal	cross
The greatest length, m	600-800	400
The smallest length, m	300-400	300
Maximum water consumption 1/sek	60	40
Minimum water consumption 1/sek	10	10
The distance between The temporary ditches, m	70	According to the length of the furow

In Uzbekistan for irrigating crops КОП-500А, КЗУ-0,5, КПУ-2000А, КБН-0,35, КЗУ-0,3 branded ditch excavators dig the ditches, dig up the soil along the ditches as well as smooth and provide the slope of the ditches . These ditch excavators have also some disadvantages. For example, these ditch axcavators need much energy for digging out the ditches on hard surface of the ground. The amount of large lumps increases, as a result, the quality of the softening decreases and as a result of deformation of the equipments of excavators. They lose geometric shapes. Magnitude of resistance force of the soil and requiring considerable effort to lay the working equipment during excavation are main disadvantages. Taking into account the aboves, in order to improve the productivity of the temporary ditch excavator, two straight disks are mounted at a certain distance to the forward part of the overturner of the excavator for reduction of the soil softening resistance and improvement quality of the soil fraction and the slope of the ditch . (1-a,b picture)



1-picture. Overview of improved temporary ditch excavator.
a-Side view of improved temporary temporary ditch excavator
b-Front view of improved temporary ditch excavator

Skill Extraction of The Skillful Operation

Generally, the hydraulic excavator is operated by handling two levers independently for four directions except crawler. Therefore, the operation becomes complex, and work efficiency is affected by operator's skill level. It is thought that the skillful operators maneuver each part of the excavator by sensing variation of ground condition, soil

(a) Excavation work
(b) Scooping work
(c) Formation work

Fig.3 Categorize of the construction work property, reaction force and relative position from the excavator and the ground. We interviewed a skillful operator to know the reason of his efficient works. A part of result is shown in Table 1. We obtained the qualitative answers that the operator acquired the skill from the empirical knowledge by the operation work for many years. However, it is not a quantitative answer of what the factors are connect for efficient work. This is considered that the operator doesn't maneuvers the excavator consciously, but unconsciously based on their empirical knowledge. Therefore, it is important to analyze the skillful operation in order to know the factor of high efficient work.

The concept of our approach is shown in Fig.2. In this paper, we use a backhoe as the hydraulic excavator and compare the difference of the operation skills between skillful and non-skillful operators, by analyzing their operations to extract the factor of high efficient work. The noticed matter is difference according to the work category, we categorize the construction work into three categories as shown in Fig.3.It is established of our research target to excavation work as (a), because (a) is essential and important work. Scooping work as (b) and formation work as (c) are not our research target. Additionally, it is defined the skillful operator experience about more than ten years,

Table1 A part of result of interview to skillful operator

Q1: What work are the most frequent by the excavator? A1: Digging work.
Q2: What is attentive when excavate? A2: Don't consider much. Excavating until not easy to excavate
Q3: What is the definition of efficiency? A3: Time efficiency.
Q4: Where do you dump the soil? A4: Swing to the left and dump soil to the left of the working area.
Q5: How much experience is needed to become skillful operator? A5: About ten years.

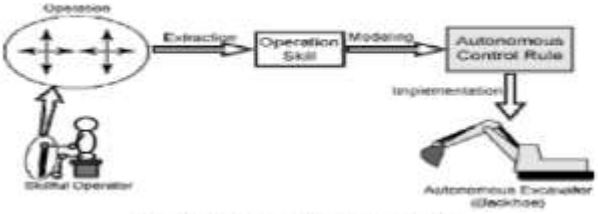


Fig.2 An approach of our study

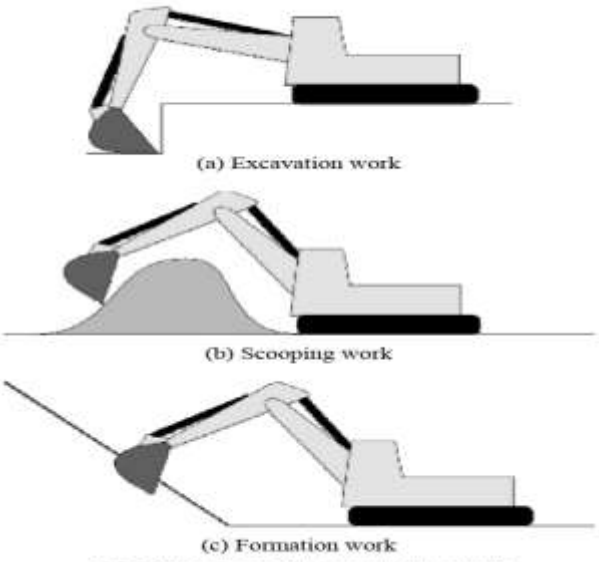


Fig.3 Categorize of the construction work

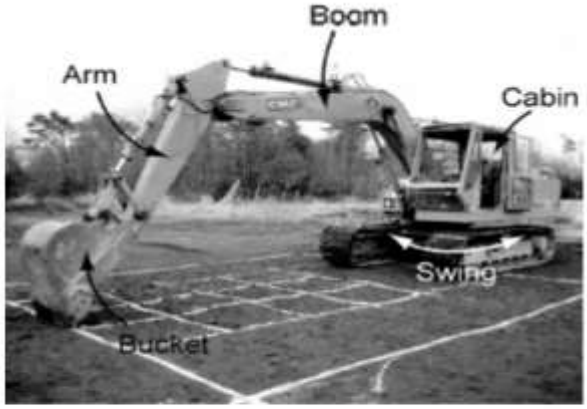


Fig.4 The appearance of the backhoe

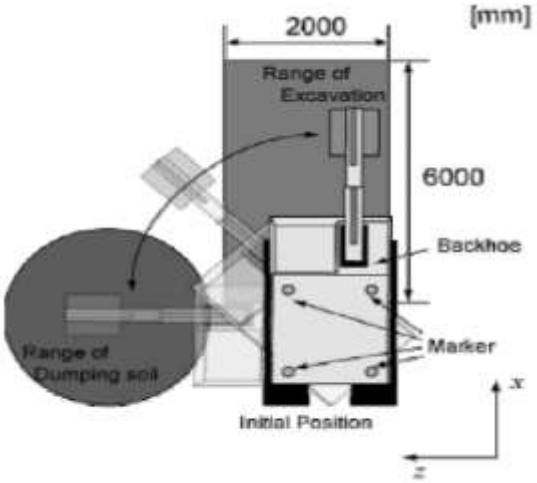


Fig.5 An environment of excavation work

and non-skillful operator experience less than it from a interview result.

Experiment

Outline of experiment

Appearance of the backhoe(SK05, KOBELCO) used for experiment is shown in Fig.4. Each link of the backhoe is fixed according to orientation of the bucket because the mechanism of the backhoe is not redundancy. Therefore, it is assumed that the difference of the operation skill between skillful and non-skillful operator is revealed to trajectories of the bucket. Then, we carry out the experiment to measure trajectories of the bucket. Experimental set up

Experimental condition

In this experiment, both skillful and non-skillful operators maneuver the same backhoe at the same working environment which is shown in Fig.5. The operators cannot excavate the all depth range of this environment by one time, and the excavation range is not determined. Therefore, it is expected that the difference of the operation of the skillful and non-skillful operator is revealed greatly.

Measurement data and system configuration

Fig.6 shows the measurement system for collecting data to derive trajectory of the bucket. The backhoe moves by expanding and contracting a boom, arm and bucket cylinder. Therefore, the displacement sensors are implemented on each cylinders, then boom

cylinder length l1, arm cylinder length l2 and bucket cylinder length l3 was achieved. The angles of crawler-cabin, cabin-boom, boom-arm and arm-bucket are calculated. Moreover, the angle of each joint q1, q2 and q3 is derived from l1, l2 and l3. It is defined the line that connected the arm-bucket joint with tip of the bucket as trajectory of the bucket. During experiment, it is recorded by video cameras for evaluating the operation and confirming consistency between operation input and actual

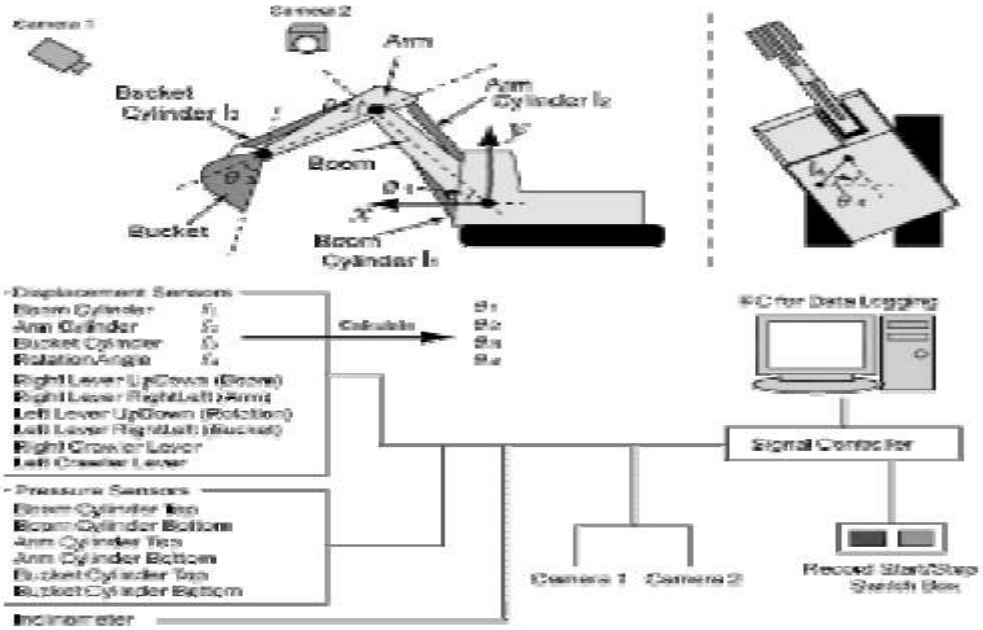


Fig.6 Configuration of measurement system

The content of work is to repeat excavating and dumping the soil. The cabin of the backhoe used for this experiment placed on its left side. From section 2, it is known that swinging and dumping the soil to left by interview to the skillful operator because it is easy to confirm the dumping range. Therefore, in this experiment, the operator swing to left and dump the soil to a free place, to ensure the correspondence of the operation. Measurement parameter is the implemented sensory data, the initial position of the backhoe, and size of excavation range at the end of work.

Experimental Result

From the start to the end of work, both operators excavates, forms and improves at the same time, it was not fixed the trajectories of the bucket. However, both operators excavates mainly several times from the start. In this paper, we target from first to eighth trajectories of the bucket. The skillfuloperator operates the arm widely about 100[cm] on the average, meanwhile the non-skillful operator operates narrowly about 40[cm] on the average. Furthermore, excavation length of the skillful operator is longer than non-skillful operator, skillful operator's length is about 290[cm] meanwhile non-skillful operator's length is about 200 [cm]. Additionally, excavation depth of the skillful operator is shallower than non-skillful operator, skillful operator's depth is about 75[cm] meanwhile non-skillful operator's depth is about 90[cm]. That is to say, the skillful operator excavate widely and shallowly from depth side.Bucket entrance angle at excavation start point of the skillful operator is nearly horizontal, meanwhile the non-skillful operator's bucket entrance angle is nearly vertical. These results are concerned with the load to the bucket. It is considered that the skillful operator maneuvers becoming small load for excavation work. The bucket can be moved faster when the load is small, so it can be achieved high work efficiency.

The bucket angle to ground by the skillful operator at the bucket pull up sequence is kept more than the bucket angle by the non-skillful

operator is nearly horizontal. If the bucket is pulled up horizontally, the bucket convolute the soil outside of the excavation range, and the range is excavated rather widely. Therefore, it is considered that this bucket angle is concerned with the precision of doneness. It was compared the excavation frequencies by both operators for one minute. As a result, the skillful operator excavates 2.8 times, meanwhile the non-skillful operator excavates 2.2 times, it is revealed to 0.6 times. Therefore, the bucket trajectories by the skillful operator maneuvers are the better to efficient work. It is thought that efficient work can be achieved to apply the control method of follow these trajectories for the unmanned excavator system.

Conclusion

In this paper, we extracted the skillful operation skill based on an autonomous excavator control system with efficient operation function. We compared the operation result of the skillful with the one of non-skillful operator. As the results, we confirm below points.

- Excavation length of the skillful operator is longer than non-skillful operator, skillful operator's length is about 290[cm], meanwhile non-skillful operator's length is about 200[cm].
- Excavation depth of the skillful operator is shallower than non-skillful operator, skillful operator's depth is about 75[cm], meanwhile non-skillful operator's depth is about 90[cm].
- Bucket entrance angle of the skillful operator is nearly horizontal, meanwhile the non-skillful operator's bucket entrance angle is nearly vertical. Quantitative evaluation of work efficiency, extraction the planning method of how to excavate, implementation of the backhoe autonomous control method apply to extracted skillful operation, is our future works. The improved ditch excavator includes the frame 1, the frame of main working equipment 2, the overturner 3, rotating two straight disks which are mounted at a certain distance between each other to the forward part of the excavator 4, lemex 5, equipment for condensation bottom of ditch 6, the rack which disks mounted 7. The straight disks are mounted on the racks using a connecting arrow. The technological process of the improved ditch excavation is as follows: During excavation, the working equipment is mounted on the back of excavator by hanging and put into operation. Due to the forward movement of the tractor, the working equipment is lowered to a certain depth in the soil. In the process of digging a temporary ditch the straight disks, which are located at a cartain distance, are buried in the soil. And the disks move around their axis. The disks cut the soil layer in front of the overturner of the excavator at a specified depth. The crushed soil layer is pushed to the side with the help of the overturner and the ditch is ready. As can be seen from the aboves, the force resistance will be reduced during digging process of the ditch excavator with the straight disks. In the process of excavation, a qualitative ditch is formed by the dislocation of of the soil layer with disks, providing the slope and geometrical shape of the ditch. Dogging temporary ditch with the ditch excavator improved with disks will reduce energy consumption and increase productivity by 8 to 10 percent

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