

# Experimental Study of Hardness Measurement affected by a Cushion between Probe and PTF Pressure sensor

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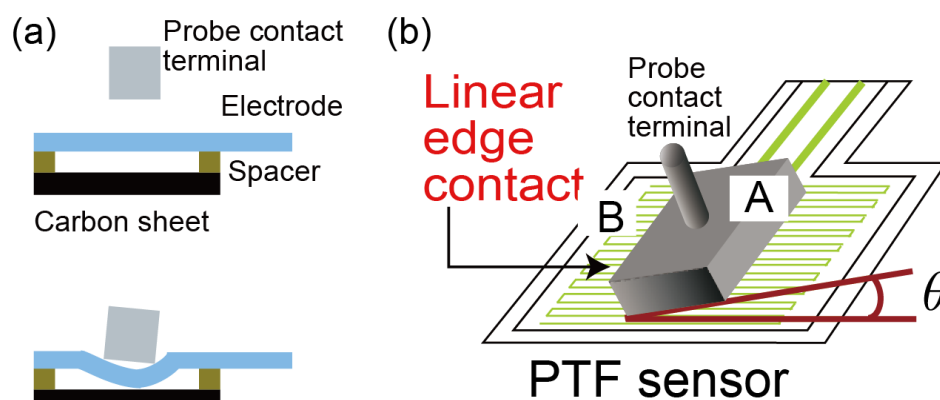
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**Abstract**—In this paper, experimental study of hardness measurement process affected by a cushion between the probe and PTF (polymer thick film) pressure sensor was discussed. Hardness sensing for soft material has been one of the important problems in many fields such as foods industry and material science. One difficulty is how to measure the weak contacting force (0.1 to few N) stable with the small target deformation by low-cost force sensor such as PTF, and we found the result of the measurement stability depending on a cushion between the probe and PTF sensor. The result shows that (1) the output force value depends on the kind of cushion material (plastic, urethane, rubber, styrene elastomer, etc.), (2) the force value was affected by the sensor probe angle to the target material. This result would be useful to develop and study the hardness sensing process intending to reduce the target deformation.

**Keywords**—Hardness measurement, soft material, cushion, PTF sensor.

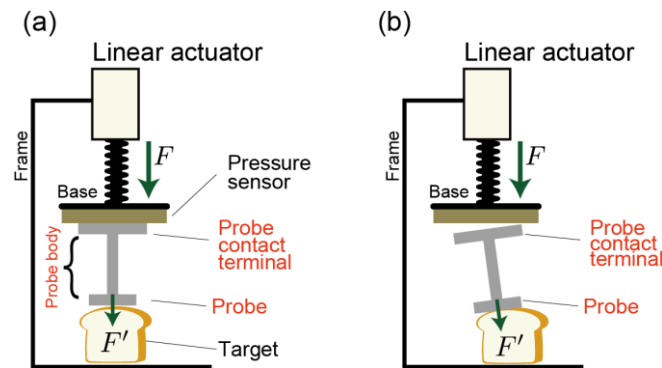
## I. INTRODUCTION

In this paper, hardness measurement process affected by a cushion between the probe and PTF (polymer thick film) type pressure sensor was discussed. Hardness sensing especially for soft material is one of important problem in many fields such as foods industry and material science, including robotics [1-11]. For application, the hardness sensing used many fields such as breast cancer diagnosis [6, 12], tension-type headache from the musculoskeletal complaints [13, 14], trapezius muscle hardness changes from the reason of visual display terminal height [15], muscle hardness measurements using ultrasound [16, 17], hardness sensing using optical (IR frequency) techniques [18]. As the force sensor, gauge sensor has been used for the hardness measurement. Since gauge sensor measures a distortion of metal, the accuracy of weak force range (0.1 to few N) inevitably drops, and it is considered difficult to measure the hardness of soft material [3,19-28]. PTF sensor, on the other hand, is designed for weak force range (about 0.1 to 20 N), but the high reliability could not be realized by the instability of the contact area change of the two membranes inside the sensor (Fig. 1a). For example, if the shape of the probe contact terminal to the PTF sensor surface (A) is square, the sensor would be pushed by the linear edge (B) of the probe contact terminal (Fig. 1b), and the probe pushing contact area of the membrane is difficult to change linearly by the pushing force. Since the force is measured proportionally the contact area of the two membranes, the shape and contact area change stability of the probe contact terminal is important factor.

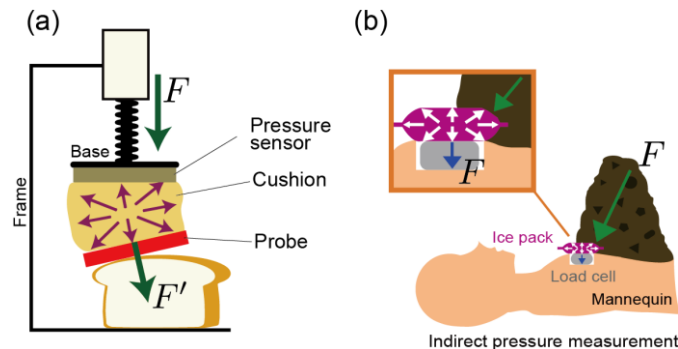


**FIGURE 1. EFFECT OF THE SHAPE OF THE PROBE CONTACT TERMINAL CONTACTING WITH PTF SENSOR SURFACE**

As shown in Fig.2a, hardness meter is developed by frame, actuator, pushing base, pressure sensor, and “probe body.” The probe body contact to the pressure sensor surface and target via the probe part simultaneously. To measure the target object hardness, the actuator force is conveyed to the target via the probe body, and contact situations of the probe body (angle, position, contact place of the target and sensor surface etc.) affect the accuracy and stability of the hardness measurement (Fig.2b). Also, the contact situations cannot control.



**FIGURE 2. EFFECT OF SHAPE OF THE PROBE CONTACT TERMINAL OF THE PROBE.**



**FIGURE 3. (a) ROLE OF THE CUSHION BETWEEN PTF PRESSURE SENSOR AND TARGET MATERIAL. (b) INDIRECT PRESSURE MEASUREMENT OF HUMAN BODY (MANNEQUIN) WHEN SEDIMENT DISASTER BY USING AN ICE PACKS**

By adopting a rubber type cushion as the probe body (Fig.3a), it is realized to absorb unevenness of the contact situation, and the target pushing force is correctly transferred to the PTF sensor surface at least. In this paper, the effect of the existence of the cushion as the probe body is examined while the hardness measurement.

### 1.1 Probe body of cushion

As shown in Fig.2a, hardness measurement is realized by a hard material's probe body such as metal, and it is important to control and measure the displacement (indent) of the probe by the pushing force [29-31]. It can be realized by the material hardness of the probe body. On the contrary, by using the cushion as the probe body, the accuracy of the control and measurement of the displacement would be reduced. In our approach, by using a cushion that softer than a metal and harder than the target object, it is designed to perform the deformation (indent) of the target by the force while the probe body is deformed to transmit the force to the sensor surface correctly at the same time [32,33]. This approach is based on the study of indirect pressure measurement of a human body (mannequin) when sediment disaster (Fig.3b) [34]. To measure a pressured force applied to the human body by the sediment, they used a load cell buried in the mannequin. But the measurement force of the load cell is unstable, and it is impossible to measure the correct pressured force with most measurement since the applied force by the sediment is not correctly gained to the load cell's sensor part. Their solution is to use an ice pack as the probe body, and the mechanism is that the force applied to one side appears as a reaction force on each side of the ice pack.

The characteristics of the ice pack required here were as follows: (1) be able to deform but return the shape (not broken), (2) spring constant  $k$  ( $\Delta f = k\Delta x$ ,  $\Delta f$  is force change,  $\Delta x$  is displacement change) is larger than the target and lower than the metal type probe body. Necessary other characteristics as material were discussed in the result section.

## II. METHOD

Fig.4 shows the developed measurement system. It constructed from a linear actuator (RB-Fir-14, DC 12 V, 100 mm stroke, 12.0mm/sec, Actuonix Corp.), polymer thick film type pressure sensor (FSR402, 0.2 to 100N, Interlink Electronics Inc.) and small size rubber cushion (2 mm diameter, thickness 2.5 mm), and 10 k $\Omega$  slider potentiometer, 2 mm thickness acrylic plate (3 $\times$ 3cm). The cushion was positioned on the PTF sensor (Fig.4), and the kind of the cushion (plastic, rubber, gel, sponge, air cushion, ice pack) was changed in the experiment. As mentioned above, the role of the cushion is assumed to convey the correct force between the target material surface and the PTF sensor surface. The displacement of the linear actuator's

pushing distance was measured by a potentiometer inside the linear actuator (10 kΩ). The position accuracy of the potentiometer was about 0.55μm.

The controller was designed as a simple potentiometer's proportional feedback system since the linear actuator's ball screw mechanisms does not realize quick responses, and the fastest convergence time or the controllability is not required in this paper. The force sensor output was measured 12 bit AD board (Arduino Duo, Arduino Corp.) inside PC via operational amplifier OP-07. The force and the potentiometer's output sampling rate were 10 msec.

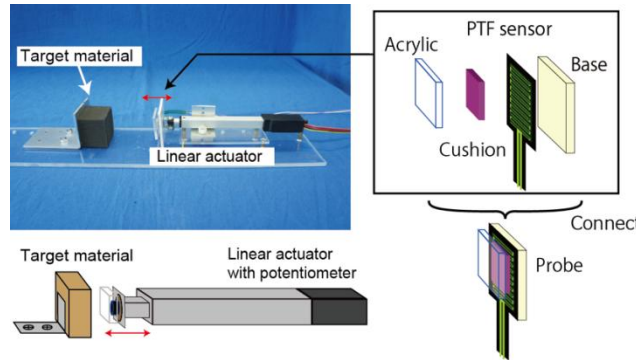


FIGURE 4. EXPERIMENT SETUP OF DEPENDENCIES OF CUSHION MATERIALS.

### III. EXPERIMENT

#### 3.1 Experiment 1: Dependencies of cushion material

In the experiment 1, the dependencies of the kind of the cushion material was examined. Table 1 shows ten material's picture and size list used as the cushion, and Table 2 means the material, product name and rough estimate of Young's modulus. As target material, urethane foam sponge (30×30×50 mm, Young's modulus  $\sigma$  about 20 kPa, No-#1, Yahata-neji Corp.) was used, and the key point of the target material was that the  $\sigma$  was lower (about one tenth) than the cushion material  $\sigma$ .

TABLE 1  
SPECIFICATION OF CUSHION MATERIALS

Name	Beads1	Beads2	Rubber1	Rubber2	Sponge	Air Cushion	IcePack	Plastic plate	Gel1	Gel2
Picture										
Shape						Soft	Soft			
Diameter (size)[mm]	4.1	7.9	11.2	9.5	20	10	32×31	9×9	9×9	30
Thickness [mm]	4.1	7.9	5.1	3.8	2.0	3.0	9.0	3.0	3.0	3.0

TABLE 2  
MATERIAL NAMES AND YOUNG'S MODULUS OF THE CUSHION MATERIALS

Name	Material	Product name, Corporation	Young's modulus [kPa]
Beads1	Plastic (PP)		~30000
Beads2	Plastic (PP)		~30000
Rubber1	Poly urethane	PS-10R, Exseal Corp.	~1000
Rubber2	Poly urethane	PS-8R, Exseal Corp.	~1000
Sponge	Urethane rubber	CN-102, Waki company	~100
Plastic Plate	Plastic (PVC)		~50000
Ice Pack	Polymeric water-absorbing polymer	HC-100PL, Catch-cool, Try Corp.	
Air Cushion	Air and thin vinyl		
Gel1	Styrene elastomer	Super gel shock absorbing sheet, ACTIKA Corp.	~200
Gel2	Urethane elastomer	GEL7, Seiwa-pro Corp.	~200

The experiment process was divided into three phases.(1) Contact phase: The sensor probe was approached to the target surface by using the linear actuator with a low speed (about 1mm/sec) and it stops the linear actuator when the force sensor changes over 6 S.D. from the 0 N. In the system, the base noise of the force sensor is 0.0005 N (6 S.D. = about 0.003 N). (2) Pushing 3 mm constant distance: The force sensor was pushed 3 mm constant distance to the target material. The linear actuator's ball screw mechanism realizes the constant distance control by not difficult control algorithm. The bang-bang control for controlling the force sensor distance was used.(3) Waiting until the force curve is attenuated: After the pushing process, the position of the sensor probe was fixed with 7 sec. The sensor probe was pushed 3 mm with the longitudinal direction of the target foam sponge (Fig.5a), and it was repeated five times. By changing the kind of cushion (Beads1 to Plastic plate), the measurement force and the stability were confirmed.

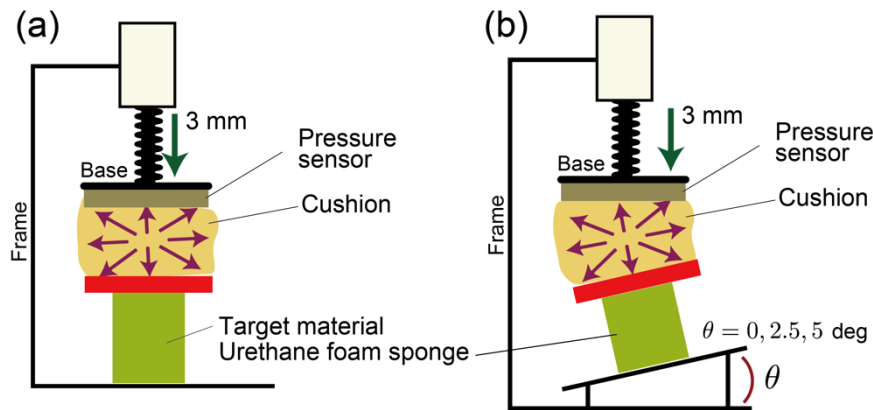


FIGURE 5. EXPERIMENT SETUP CONDITIONS OF (a) EXPERIMENT 1AND (b) EXPERIMENT 2.

3.2 Experiment 2: Dependencies of the sensor probe angle

In experiment 2, the dependencies of the sensor probe angle were examined using (a) Plastic plate and (b) Gel2 in Table 1 as the cushion. The experiment process was same with experiment 1.

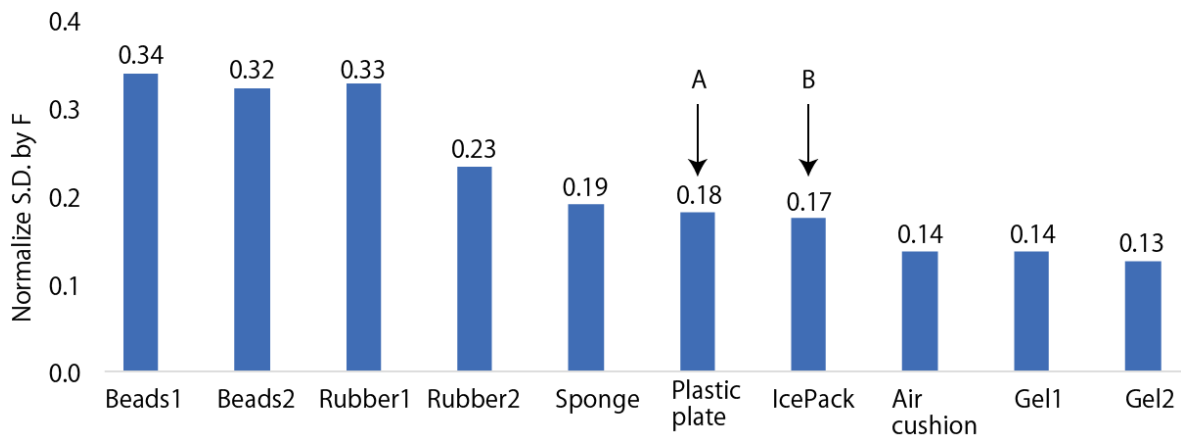
IV. RESULT

The result of experiment 1 was shown in Table 3 and Fig.6. The force  $F$  represents the average of the PTF sensor output after 7 sec attenuation when 3 mm pushing process, and S.D. of  $F$  means the standard deviation of the  $F$  (N=5). Since the  $F$  was not taken a constant value, the S.D. of  $F$  was normalized by  $F$  using formula  $\frac{S.D.of F}{F} = s$  and the result was summarized in Table 3 and Fig. 6. When the value takes a low value, it means the measurement was a stable one.

The result was summarized below: (1) When the cushion was hard material (Beads1, Beads2),  $s$  takes a high value (>0.3) though the shape of the cushion is a sphere (Table3 and Fig. 6).It means that to reduce the effect of angle dependencies of the sensor probe, the point contact (because it is a sphere) has not better effects to the sensor output of the PTF. (2)Round shape polyurethane rubber (Rubber1, Rubber2) result takes almost same or relatively small value of  $s$ . It means that in the range of 1000 kPa material, the shape of the cushion was not important. (3) To comparing the previous study of the indirect pressure measurement of a human body (mannequin) [34] (Fig.3b), small sized Ice pack (Fig. 6B) was used, and the result was good comparing with Sponge (100 kPa) or Plastic plate (50000 kPa, Fig. 6A).(4) Soft materials (Air Cushion, Gel1, Gel2) got good performance (around 0.13)of  $s$ . It means that about 200 kPa range of Young’s modulus was necessary to measure the hardness of the urethane foam sponge (about 20 kPa).

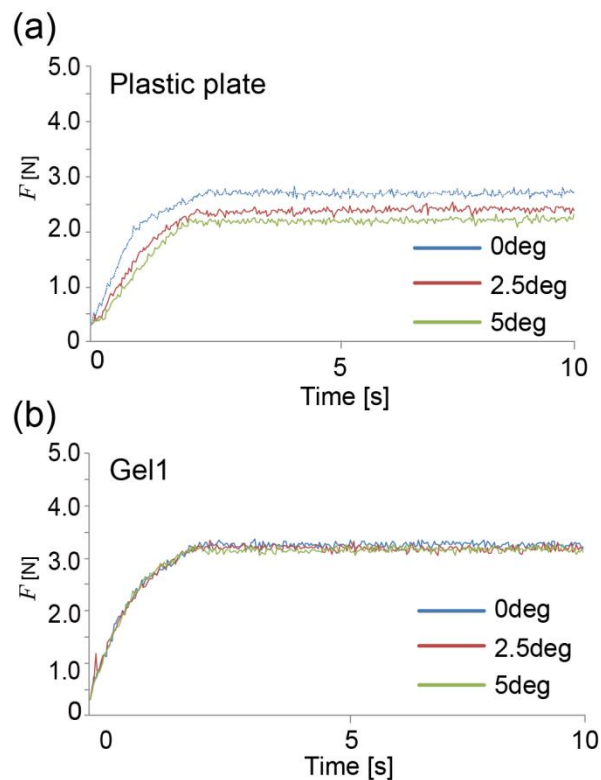
TABLE 3  
RESULT OF EXPERIMENT 1

	Beads1	Beads2	Rubber1	Rubber2	Sponge	Plastic plate	IcePack	Air Cushion	Gel1	Gel2
Picture										
F[N]	1.32	1.3	1.4	2.05	2.31	2.03	2.79	2.7	2.78	3.1
S.D. of F [N]	0.45	0.43	0.46	0.48	0.44	0.37	0.49	0.37	0.38	0.39
Normalize S.D. by F	0.34	0.32	0.33	0.23	0.19	0.18	0.17	0.14	0.14	0.13



**FIGURE 6. NORMALIZED STANDARD DEVIATION BY F OF THE RESULT OF EXPERIMENT 1**

The result of experiment 2 was shown in Fig.7. Fig. 7(a) was the case of the Plastic plate as the cushion. The output force value  $F$  was measured in the case of 3 mm pushing while 10 sec. The reason of using the Plastic plate was that even if Young's modulus takes a high value, the  $s$  was measured as a small value. This characteristic mainly depended on the size of the plate, and the  $9 \times 9$  mm size plate led maximum performance in our experimental setup (it related to the size of the PTF sensor). However, in the case of the Plastic plate cushion, the  $F$  was decreased by the change of the pushing angle (the condition was Fig.5b), and the force convergence curve was not stable. On the other hand, Fig. 7(b) shows the case of Gel1, and it was converged one value ( $3.18 \pm 0.08$  N,  $N=5$ ) in each angle settings.



**FIGURE 7. RESULT OF EXPERIMENT 2. THE CASE OF PLASTIC PLATE AND GEL1.**

## V. CONCLUSION

In this study, experimental study of hardness measurement process affected by a cushion between the probe contact terminal and PTF pressure sensor was discussed. The result of experiment 1 shows that the material kind of the cushion is important for the stable measurement of the force. Shock-absorbing gel (Gel1, Gel2) was effectively work for transmitting the pushing force to the PTF sensor surface. The result of experiment 2 shows that the pushing angle of the sensor probe was affected to the force measurement and the divergence of the force could be suppressed by using shock absorbing gel (Gel1, Gel2). This result would be useful for developing a low-cost hardness measurement system for soft material.

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