

Tools and Processes for Robotic Outfitting of Buildings Terrestrial And Space Construction Examples

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Terrestrial Vs Extraterrestrial Construction

Multi System Assemblies

Traditional Construction

Systems Integration

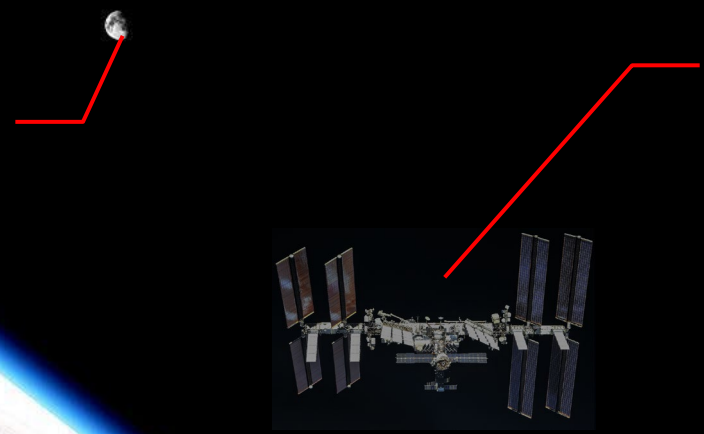
NREL ICI – Robotics for Systems Integration

Terrestrial Vs Extraterrestrial Construction

Building on extra-terrestrial bodies

a system of systems that are functional

- structurally stable
- energy efficient
- thermally efficient
- habitable****
- remotely constructable
- easily deployable
- remotely controllable



Building in orbital space

a system of systems that are functional

- structurally stable
- energy efficient
- thermally efficient
- habitable****
- easily deployable (or assembly)
- remotely controllable

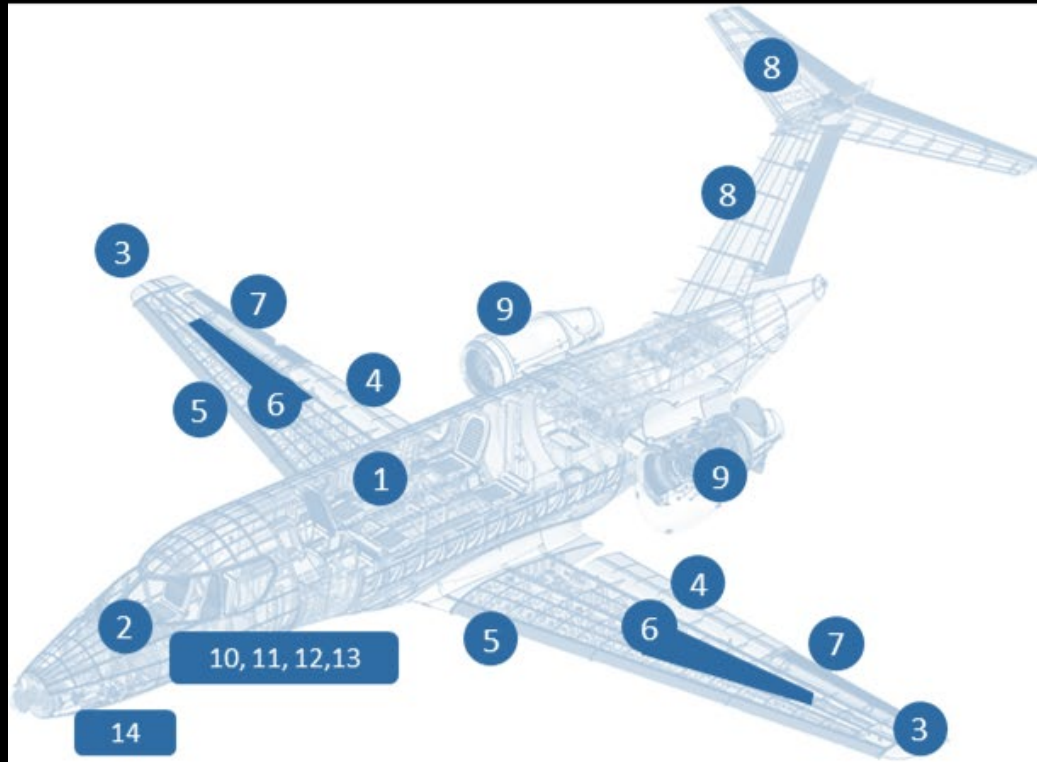
Building on Earth

a system of systems that are functional

- structurally stable
- energy efficient
- thermally efficient
- habitable****
- rapidly constructable







STRUCTURES

- 1. Fuselage
- 2. Cockpit

AVIONICS

- 3. Winglet
- 4. Flaps
- 5. Slats
- 6. Spoiler
- 7. Aileron
- 8. Stabilizers

MECHANICAL

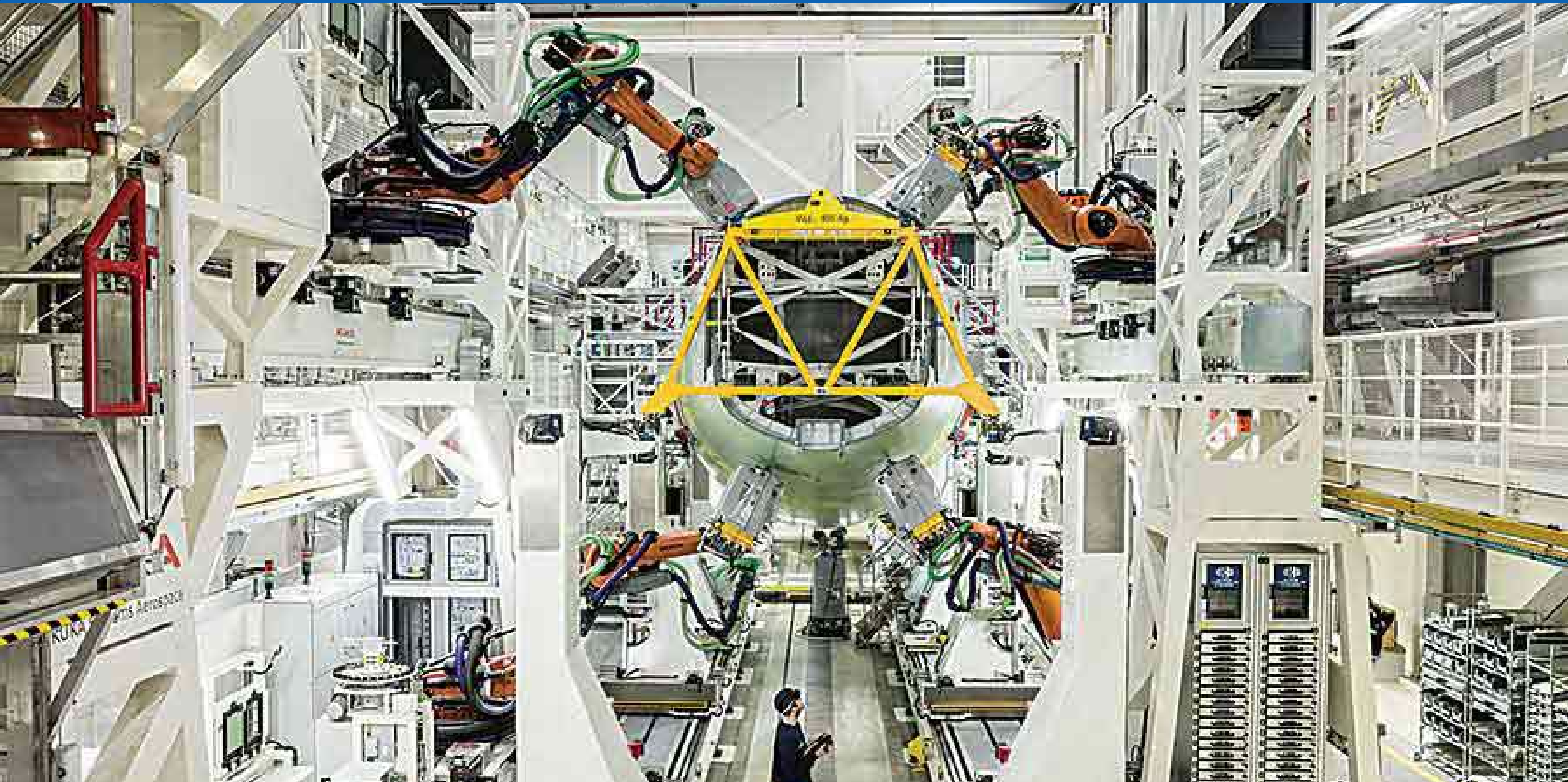
- 13. Landing Gear
- 14. Wheels

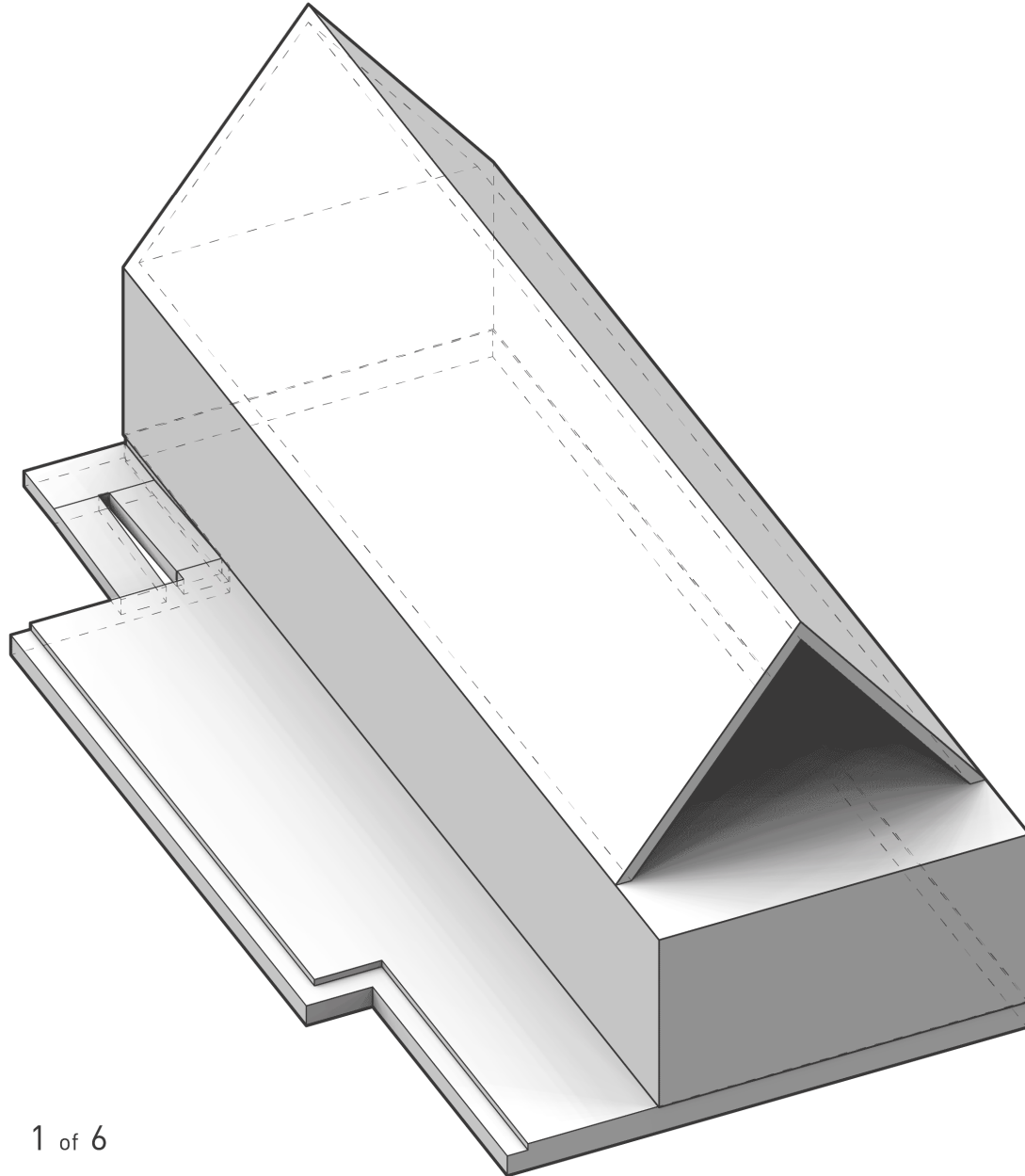
CONTROL SYSTEMS

- 10. Flap Control System
- 11. Aileron Control System
- 12. Spoiler Control System

ENGINES

- 9. Turbine





~100+
Components

MECHANICAL

- 12. Boiler Plant
- 11. Chiller Plant
- 10. Air valves
- 9. Ducts

ELECTRICAL

- 16. Main board
- 15. Power supply
- 14. Conduits
- 13. Artificial Lighting

PLUMBING

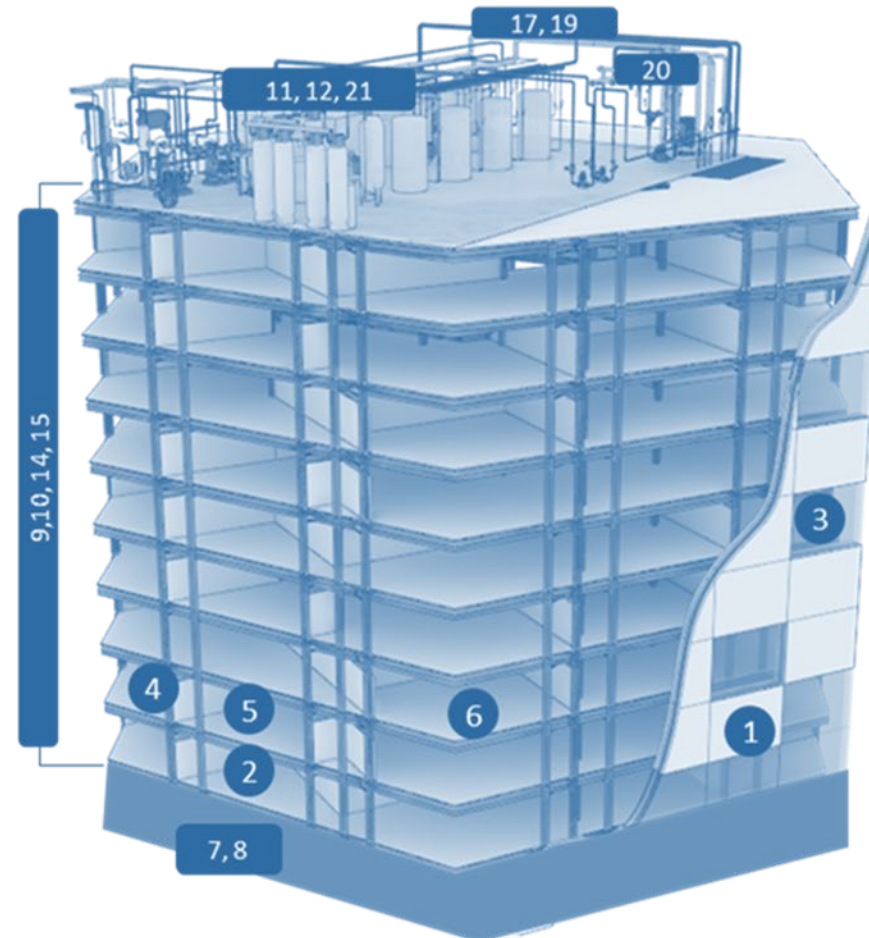
- 21. Water storage tank
- 20. Water supply pipes
- 19. Grey water return pipes
- 17. Drainpipes

STRUCTURAL

- 8. Footing
- 7. Foundation
- 6. Slabs
- 5. Beams
- 4. Columns

ARCHITECTURAL

- 3. Windows
- 2. Interior walls
- 1. Envelope assembly

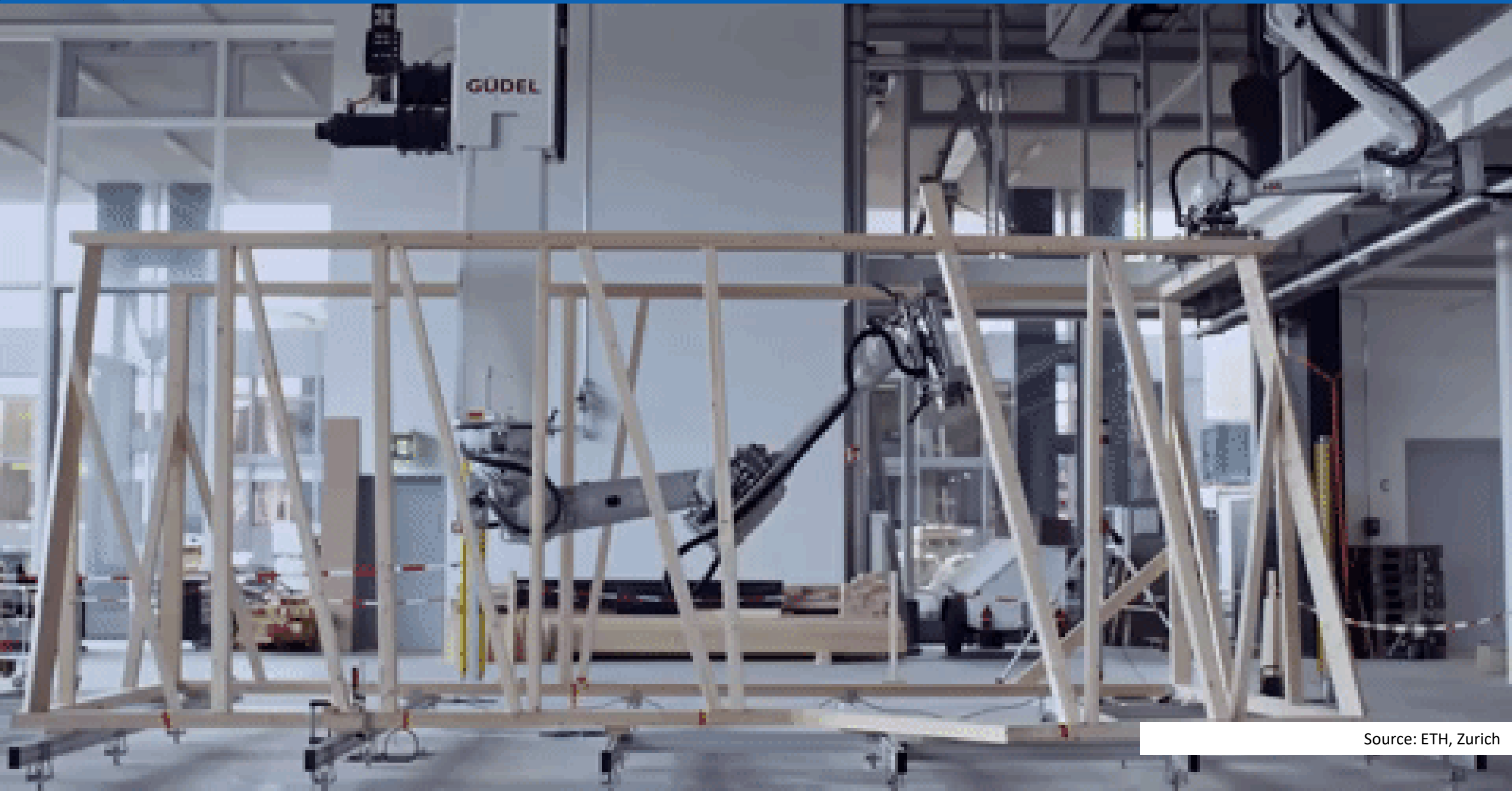


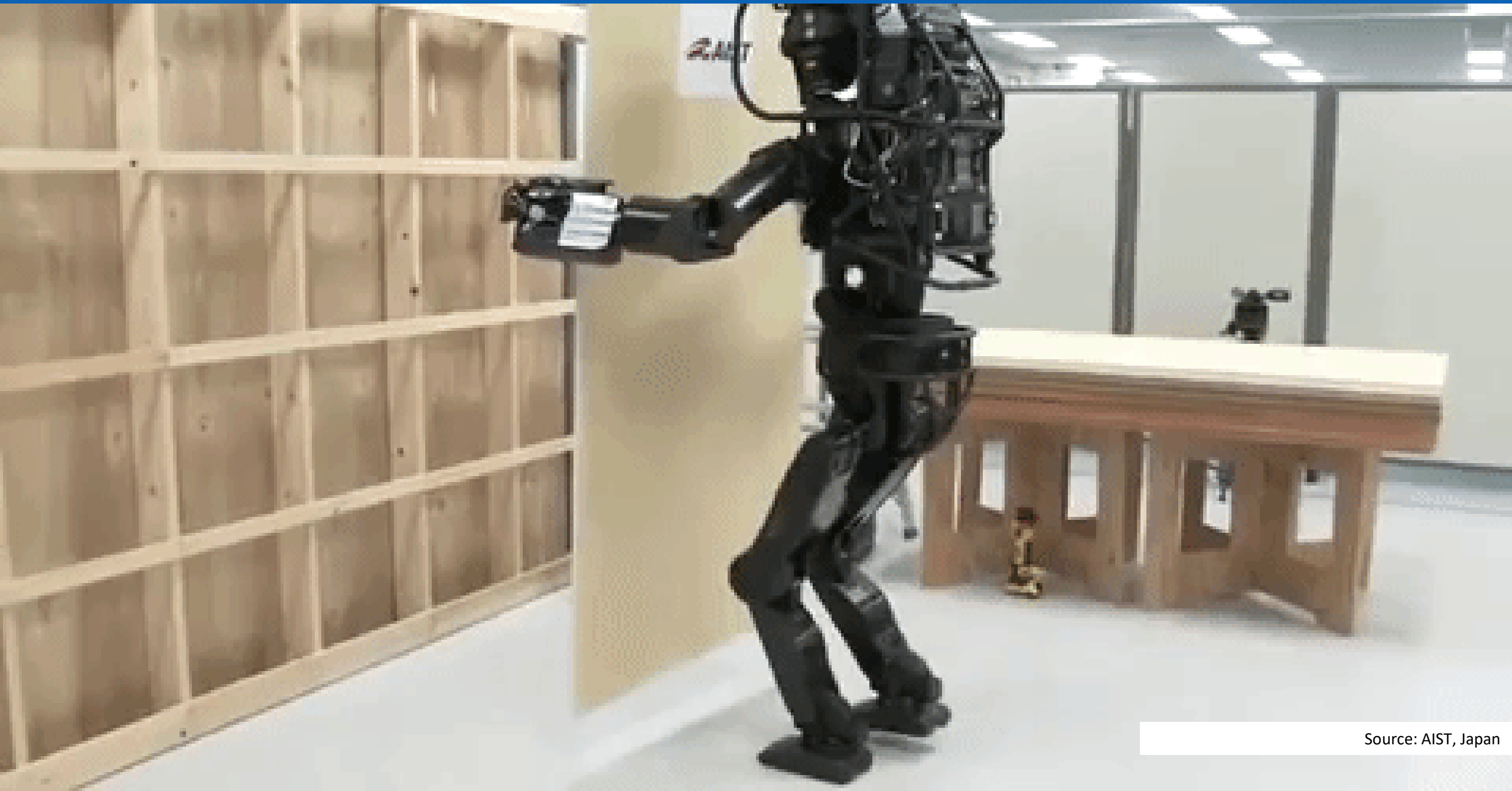
~1000+
Components



~10000+
Components















Source: Naveen Kumar Muthumanickam (Penn State at NASA 3D Printed Mars Habitat Challenge)

MECHANICAL

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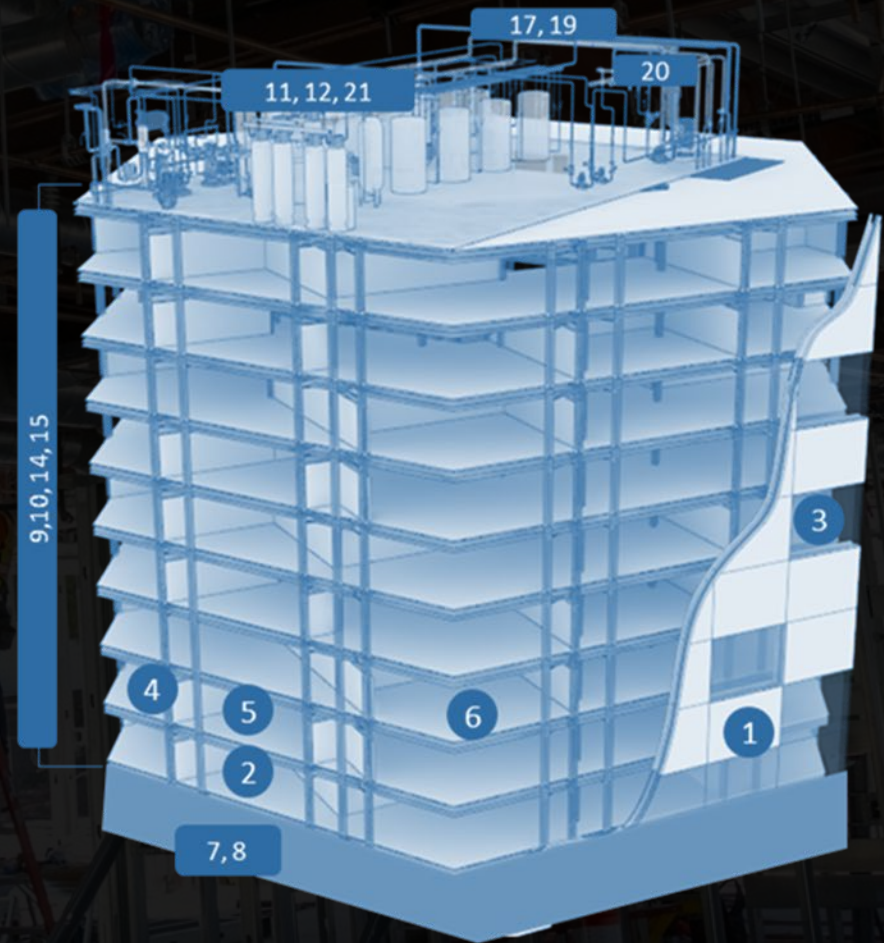
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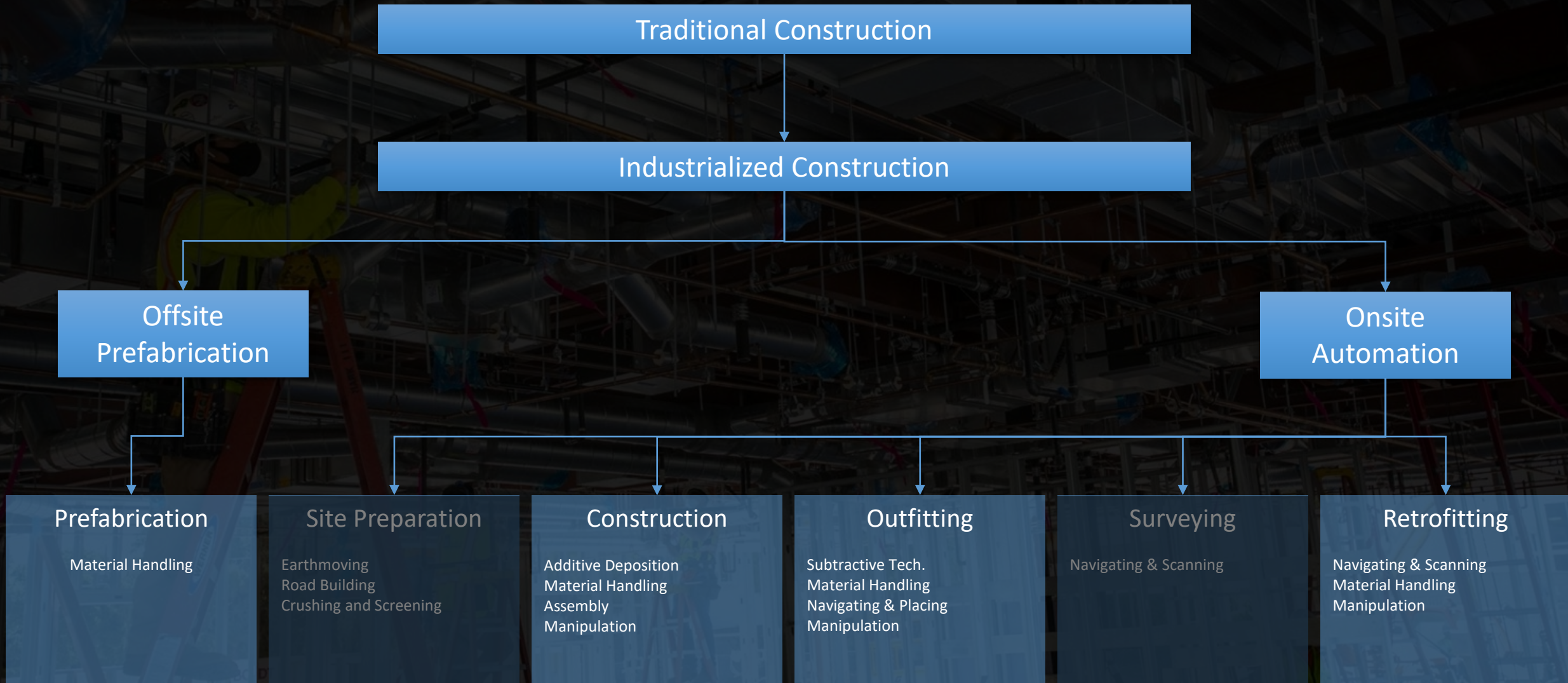
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Industrial Robotic Arms

Rovers

Quadrupedals

Drones

Robotic Outfitting

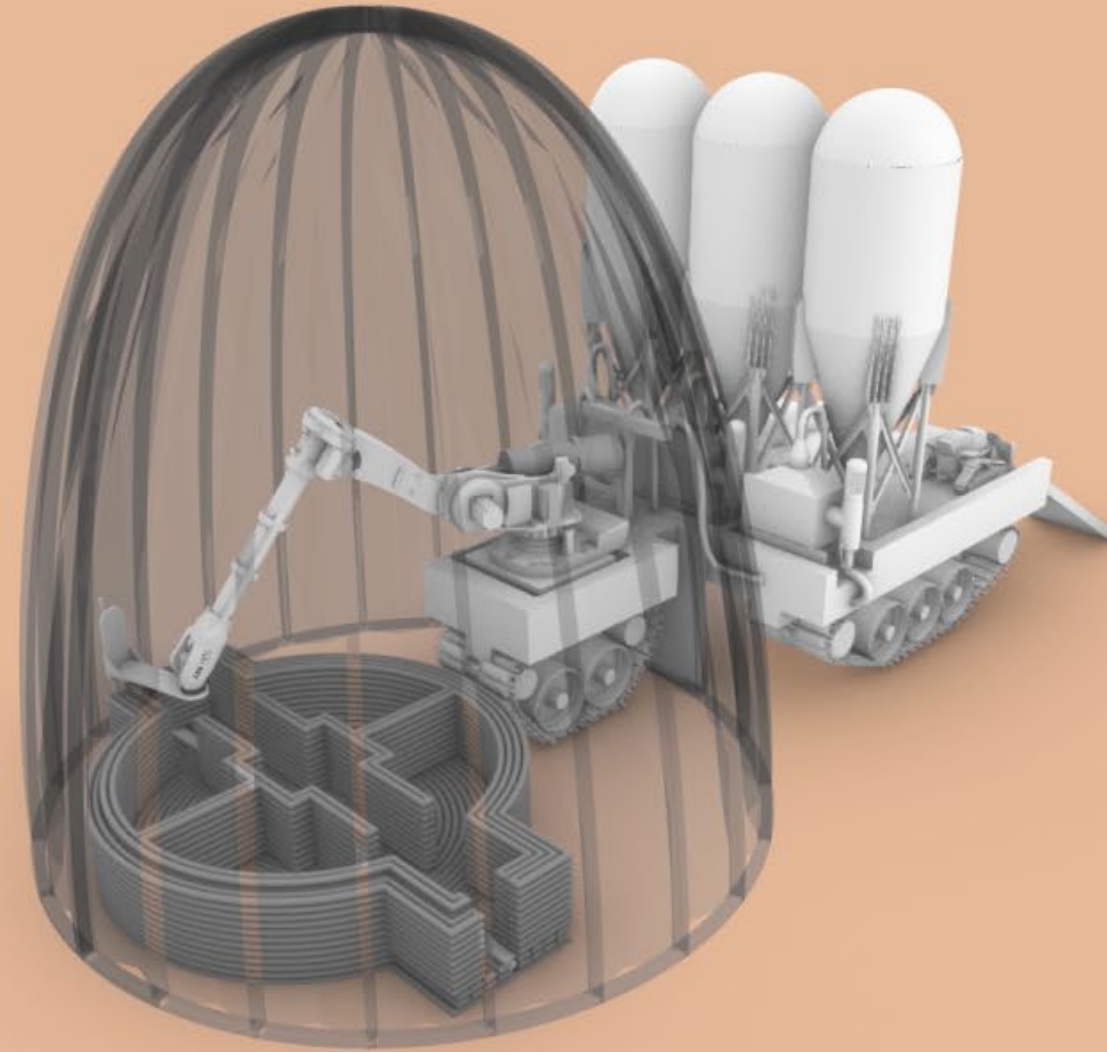
Virtual Simulation

Semi-Autonomous Robotics

Computer Vision Based Sensing

Autonomous Robotics

Digital Twin Visualization

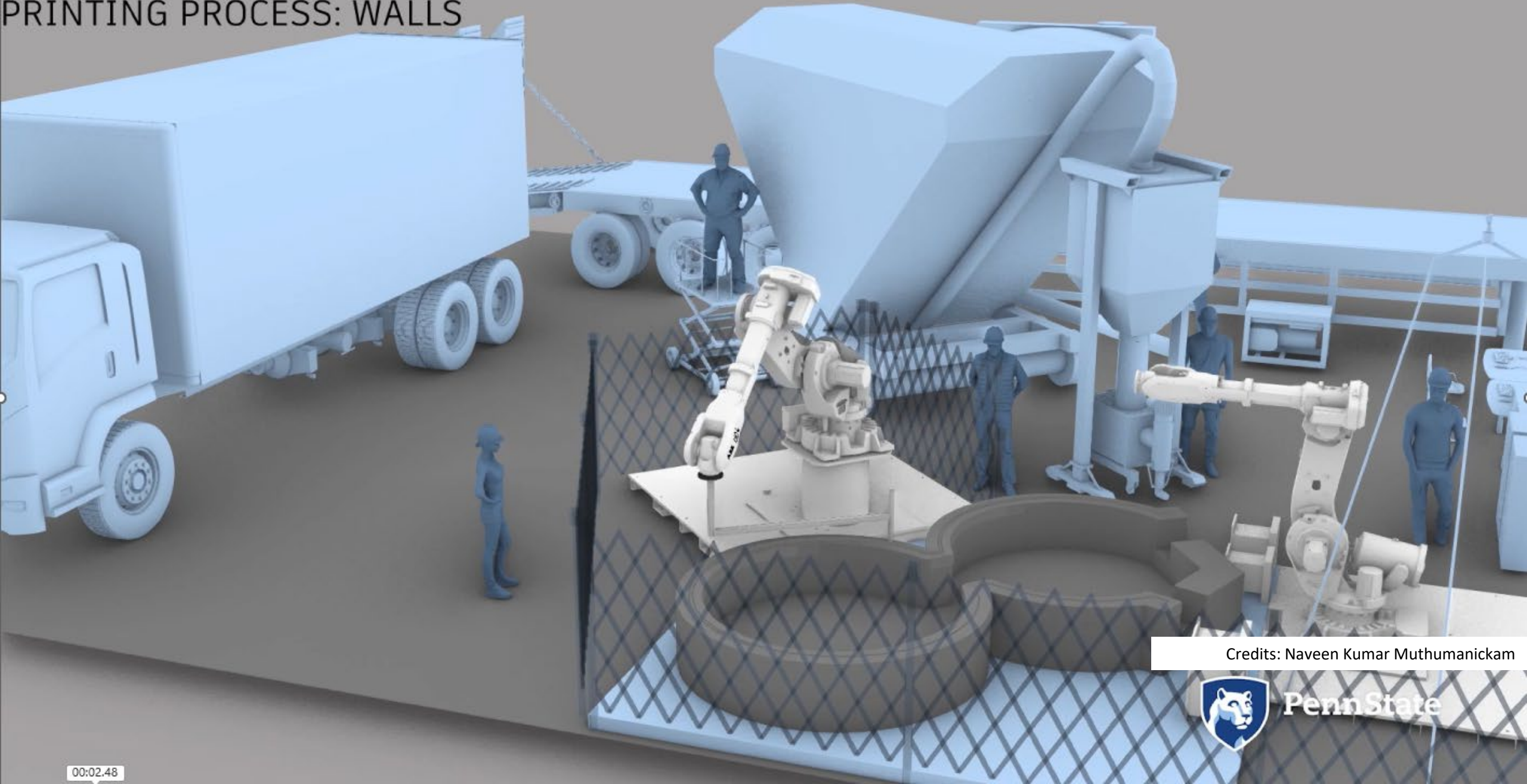


Credits: Naveen Kumar
Muthumanickam/Eduardo Castro/Negar Ashrafe



PennState

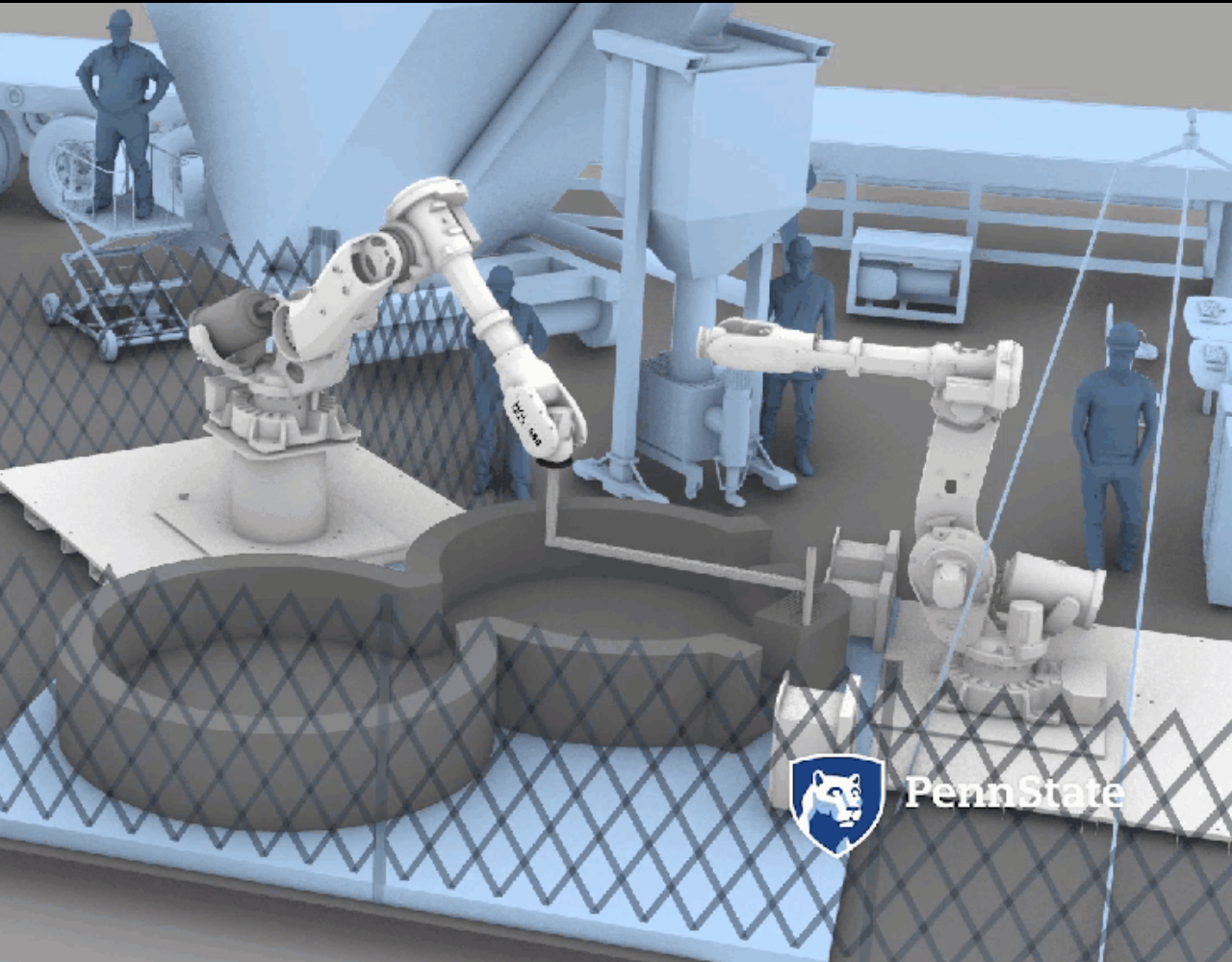
PRINTING PROCESS: WALLS



Credits: Naveen Kumar Muthumanickam



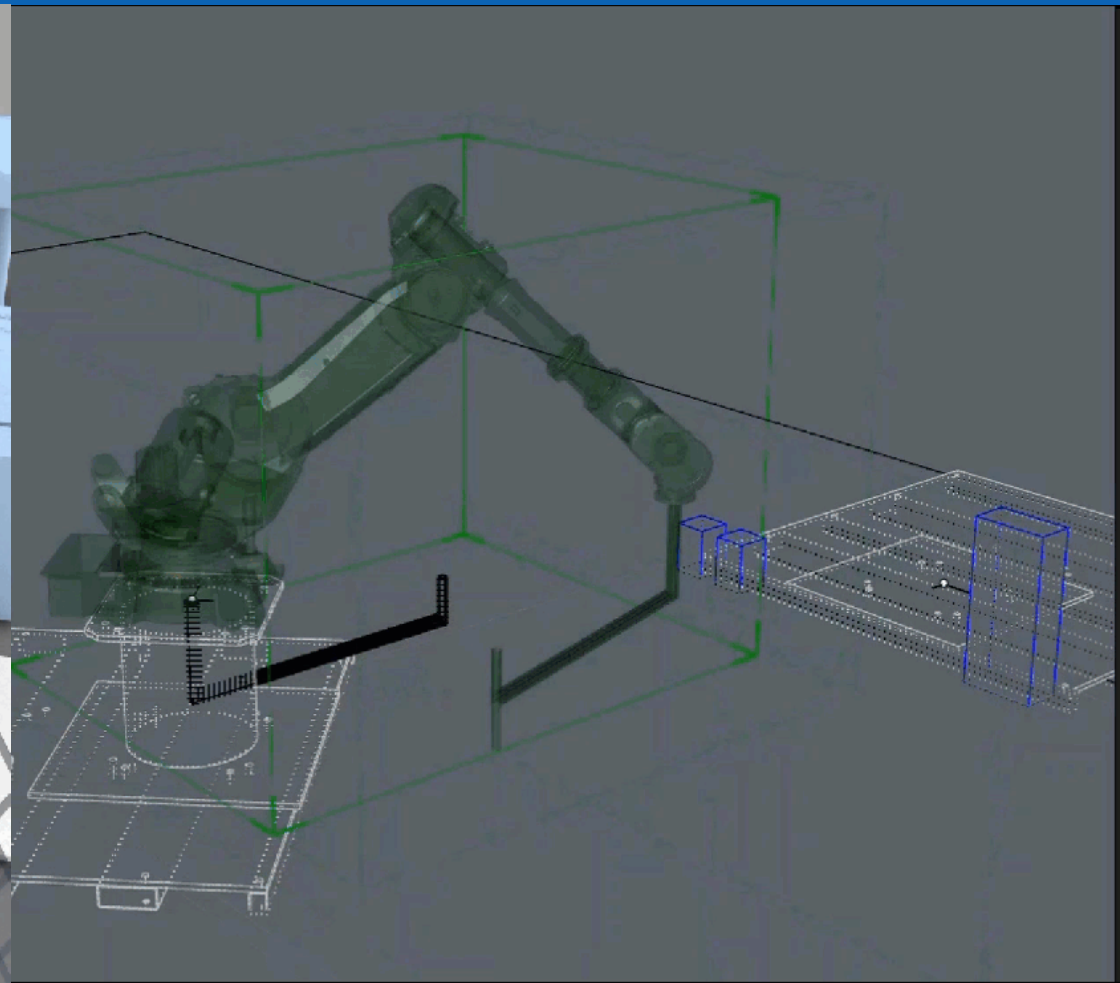
Penn State



4D Simulations of robotic construction is computational graphics intensive



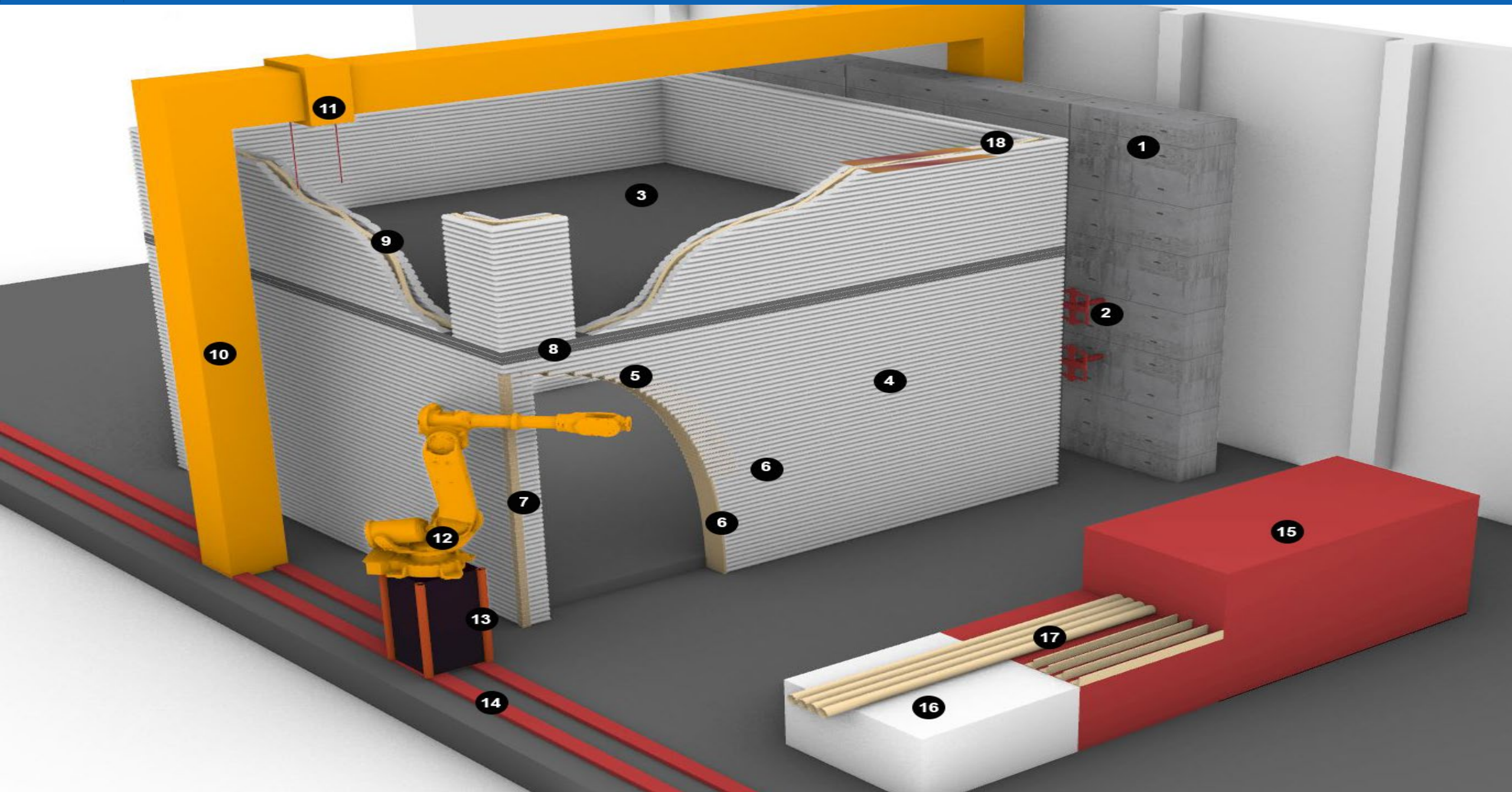
Detailed 4D Simulation

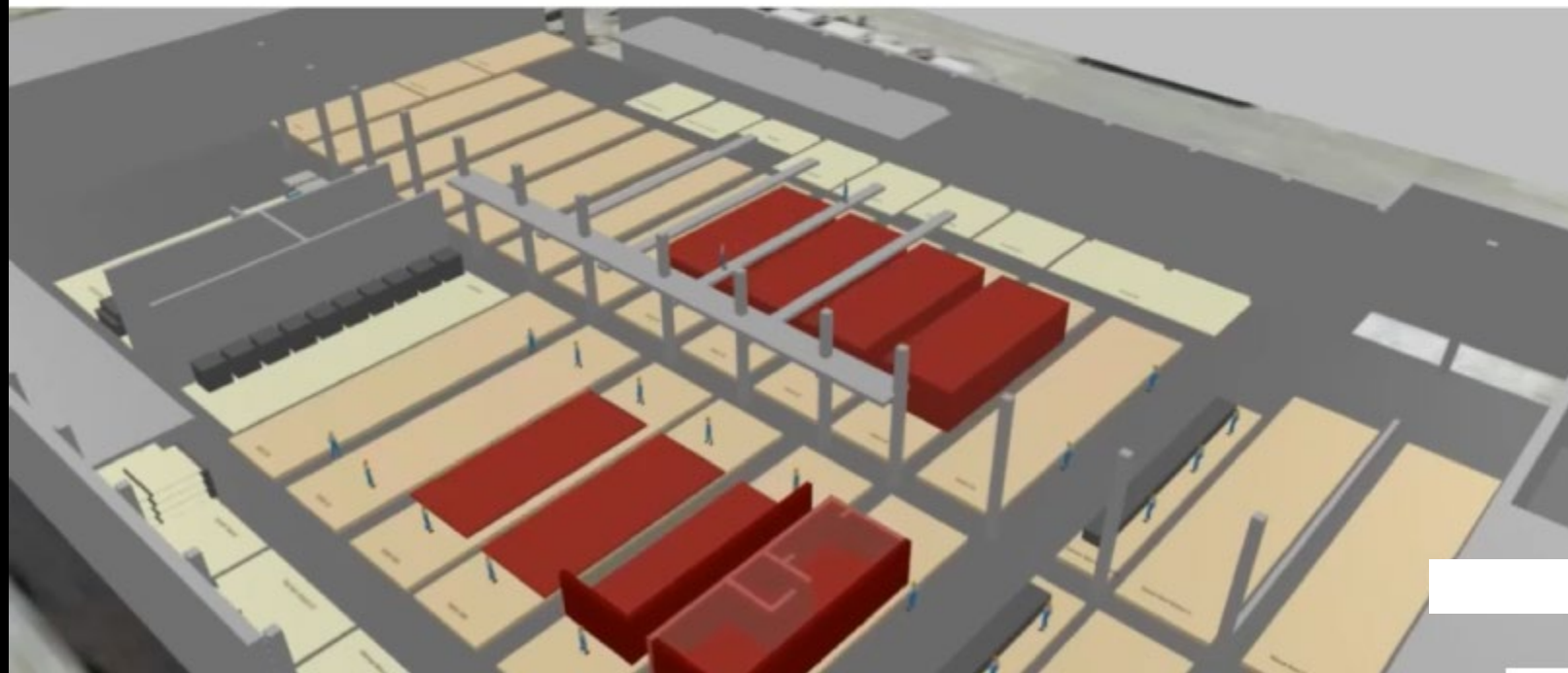
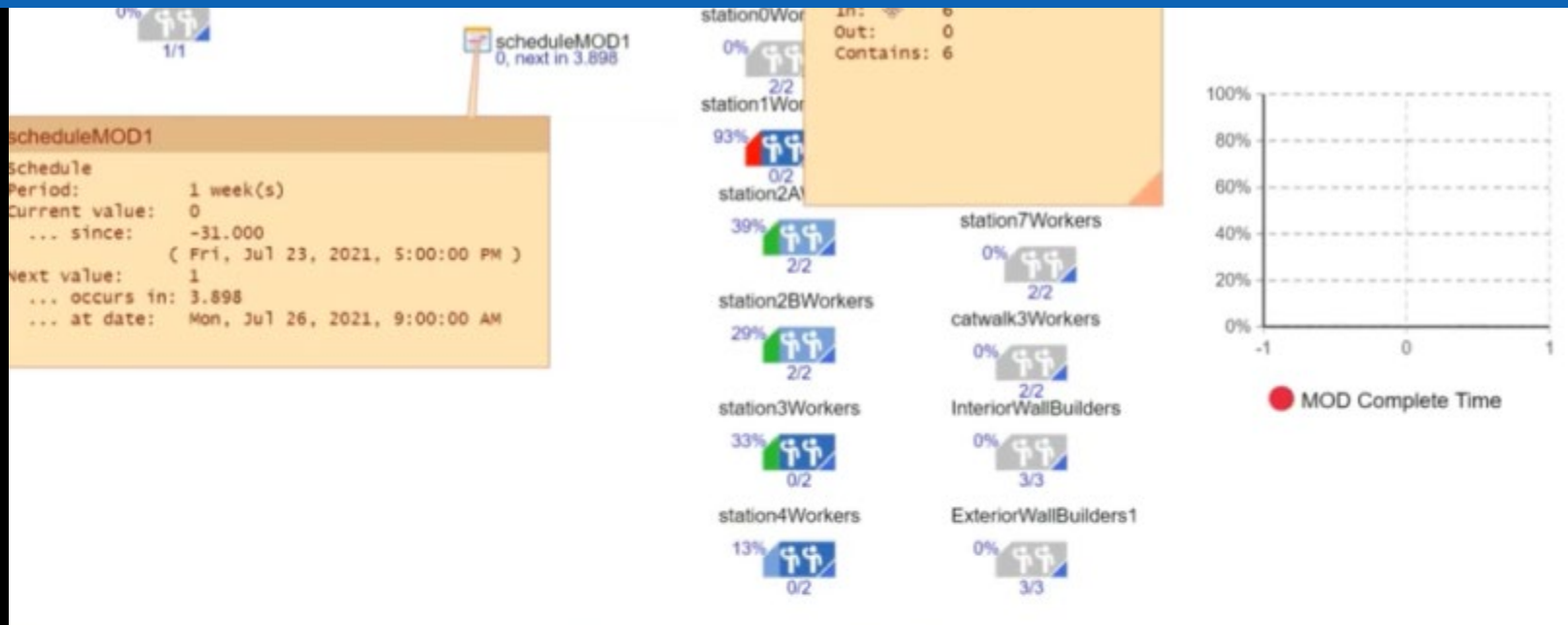


Robotic Box Collision metamodel (faster computation)

```
1 Module MoveMod
2 !Declarations
3 !tooldata
4 PERS tooldata
5
6 !wobjdata
7 PERS wobjdata
8
9 Proc Main()
10 Move;
11 EndProc
12
13 Proc Move()
14 Confl \On;
15 Confl \Off;
16 SingArea \Wris
17 MoveL [[1290.3
18 MoveL [[1272.4
19 MoveL [[1255.5
20 MoveL [[1239.6
21 MoveL [[1224.6
22 MoveL [[1210.6
23 MoveL [[1197.5
24 MoveL [[1185.3
25 MoveL [[1174.6
26 MoveL [[1153.9
27 MoveL [[1137.1
28 MoveL [[1123.5
29 MoveL [[1112.8
30 MoveL [[1105.6
31 MoveL [[1099.8
32 MoveL [[1097.1
33 MoveL [[1096.7
34 MoveL [[1098.5
35 MoveL [[1102.3
36 MoveL [[1108.6
37 MoveL [[1115.4
38 MoveL [[1124.3
39 MoveL [[1134.6
40 MoveL [[1146.3
41 MoveL [[1159.3
42 MoveL [[1173.4
43 MoveL [[1188.7
44 MoveL [[1205.6
45 MoveL [[1222.2
46 MoveL [[1248.3
```

Metamodels for faster constructability analysis (Toolpath Clash Detection)







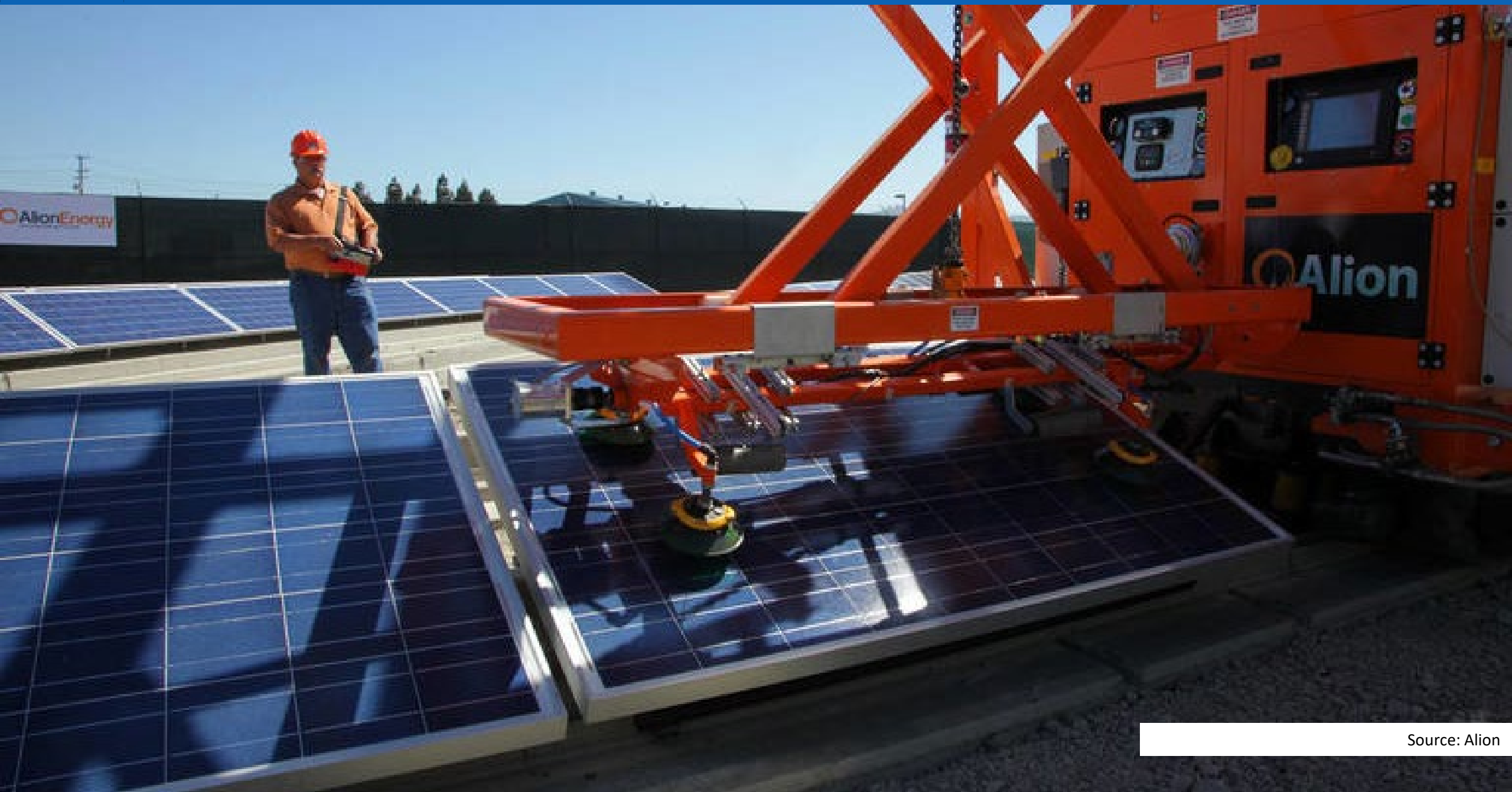














View Distance

00:04.34

Cross-section

Transparency

Credits: NREL (David Goldwasser)

Thank you!



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