

**MODELING OF INTELLIGENT SORTING MANIPULATORS FOR MULTI-PRODUCT PRODUCTION LINES**

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Abstract

This article presents the modeling and prototyping stages of an intelligent sorting manipulator system designed for multi-product production lines. During the sorting process, the manipulator performs tasks such as detecting, classifying, and directing objects of various sizes and weights to the appropriate paths. Mechanical and kinematic models of the system were developed using SolidWorks and MATLAB software, while a physical prototype was assembled using Arduino UNO and sensor modules. The sorting accuracy and time were analyzed by comparing simulation and practical experiment results. The outcomes demonstrate that this technology can operate efficiently in multi-product manufacturing and contribute to increasing the level of automation.

Keywords: Intelligent manipulator, Sorting system, Simulation, Arduino, Sensor integration, Robotics.

Introduction

In modern production lines, the diversity of product types and the differences in their geometry and physical properties place high demands on automation. In particular, there is a growing need for intelligent manipulator systems that can operate with precision, without human intervention, in tasks such as sorting, placing, or directing products of various sizes, shapes, and weights. Traditional mechanical sorting methods often fail to adapt to the rapidly changing characteristics of products and are limited in terms of efficiency. In recent years, intelligent manipulators developed based on robotics, mechatronics, and artificial intelligence have been proposed as technological solutions to this challenge. These manipulators use sensors to automatically detect objects, classify them, and perform the corresponding actions. However, before such systems can be implemented in practice, it is essential to simulate their mathematical models and operational algorithms and to test them in the form of real prototypes.

This article highlights the scientific foundations for developing an intelligent sorting manipulator system designed for multi-product production lines. The main objective of the study is to develop a mathematical model of the manipulator's movement, simulate it, and then evaluate the system's performance experimentally through the creation of a physical prototype.



Research Methodology

In this research, the development of the intelligent sorting manipulator was carried out based on a step-by-step approach. Initially, the geometric structure of the manipulator was designed using the SolidWorks software platform. A four-degree-of-freedom system was selected for its motion mechanism, and a configuration capable of performing both linear and rotational movements was developed. In describing the motion, classical robotics formulas—physical equations characterizing force, torque, acceleration, and weight balance—were employed.

To analyze and optimize the manipulator's movement, its dynamic model was constructed in the MATLAB Simulink and Simscape Multibody environments. In this simulation, the manipulator's speed, trajectory, and operational efficiency were evaluated for objects of varying weights and sizes. For each direction of movement, load conditions and variations in time parameters were theoretically calculated.

To compare the simulation results with real-world performance, a physical prototype was built.

$$\tau = J \cdot \alpha + b \cdot \omega + \tau_f$$

$$F = m \cdot a, \quad T = r \cdot F$$

The prototype was based on the Arduino UNO platform, to which IR sensors, servo motors, and control modules were connected. The software was written in Arduino C language, and the object detection and sorting algorithm was automatically controlled through this code. Once an object was detected by a sensor, the manipulator moved in the appropriate direction based on the object's physical characteristics (size and weight) and sorted it into the corresponding bin. The sorting algorithm was designed to distinguish between four main object types: small-light, small-heavy, large-light, and large-heavy. A specific trajectory and servo motion were assigned to each object type.

Deviations in accuracy and timing were observed and analyzed to identify their causes—such as sensor precision, motor torque, and weight limits. In the final stage, the experimental results were analyzed to evaluate the efficiency of the sorting system. The results from the simulation and the physical prototype were compared using charts and tables. The findings showed that although there were differences between the simulation and the prototype performance, the discrepancies remained within acceptable limits. This indicates that the proposed intelligent sorting manipulator is sufficiently reliable and effective for practical implementation.

Results and Discussion

During the study, the developed intelligent sorting manipulator system was first tested in a simulation environment and then validated through practical experiments in laboratory conditions using a real prototype. The simulation was carried out using SolidWorks and MATLAB Simscape Multibody software environments, while the prototype was tested on the Arduino UNO platform using IR sensors and servo motors. The sorting system was based on distinguishing between four object types: small-light, small-heavy, large-light, and large-heavy. A specific trajectory and servo motion algorithm were defined for each object type.

The object sorting time and accuracy results from both the simulation and the prototype were compared using the following graphs and tables.

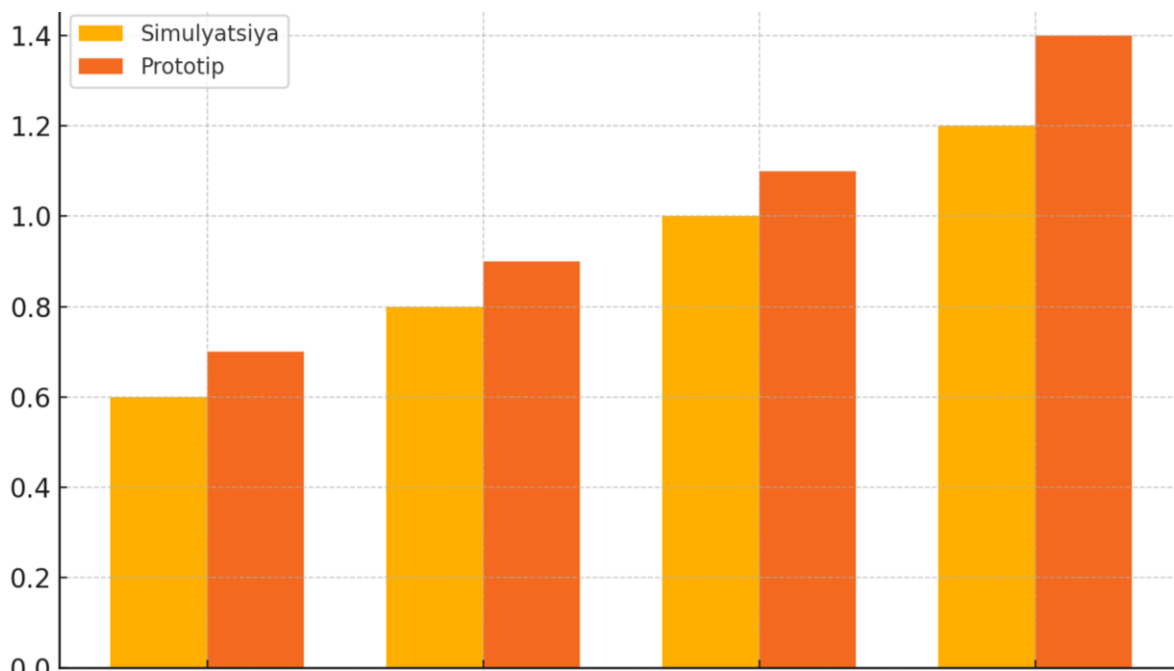


Figure 1. Comparison of Sorting Time by Object Type

In the simulation, small-light objects were sorted in 0.6 seconds, while in the prototype this time extended to 0.7 seconds. The largest discrepancy was observed with large-heavy objects: 1.2 seconds in the simulation compared to 1.4 seconds in the prototype. This difference is attributed to mechanical load, servo motor torque limitations, and the real operating conditions of the platform.

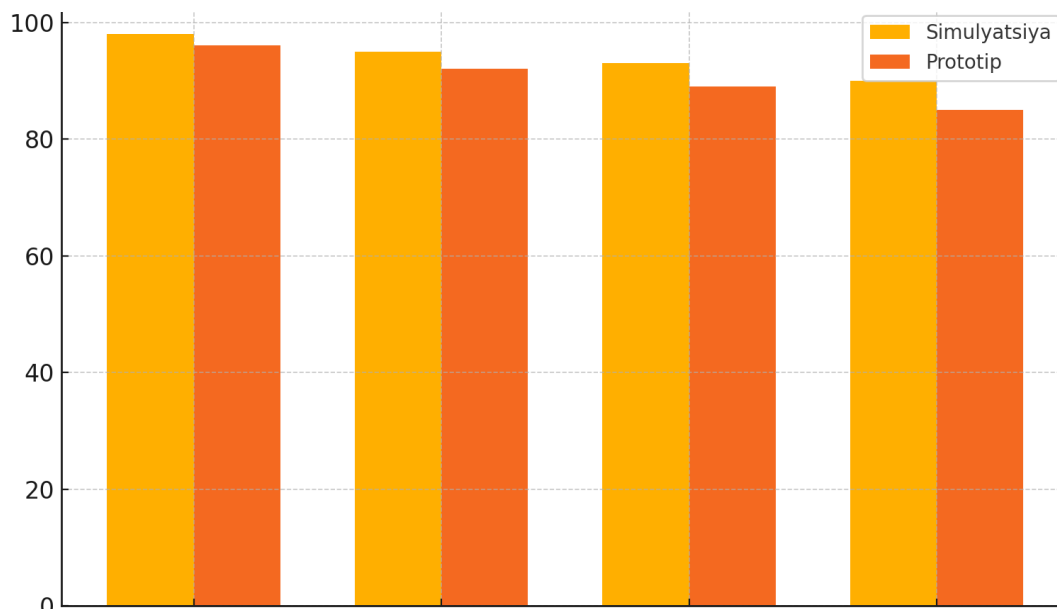


Figure 2. Comparison of Sorting Accuracy by Object Type

The accuracy indicators in the prototype were slightly lower compared to the simulation. For small-light objects, the prototype achieved 96% accuracy, while for large-heavy objects, accuracy



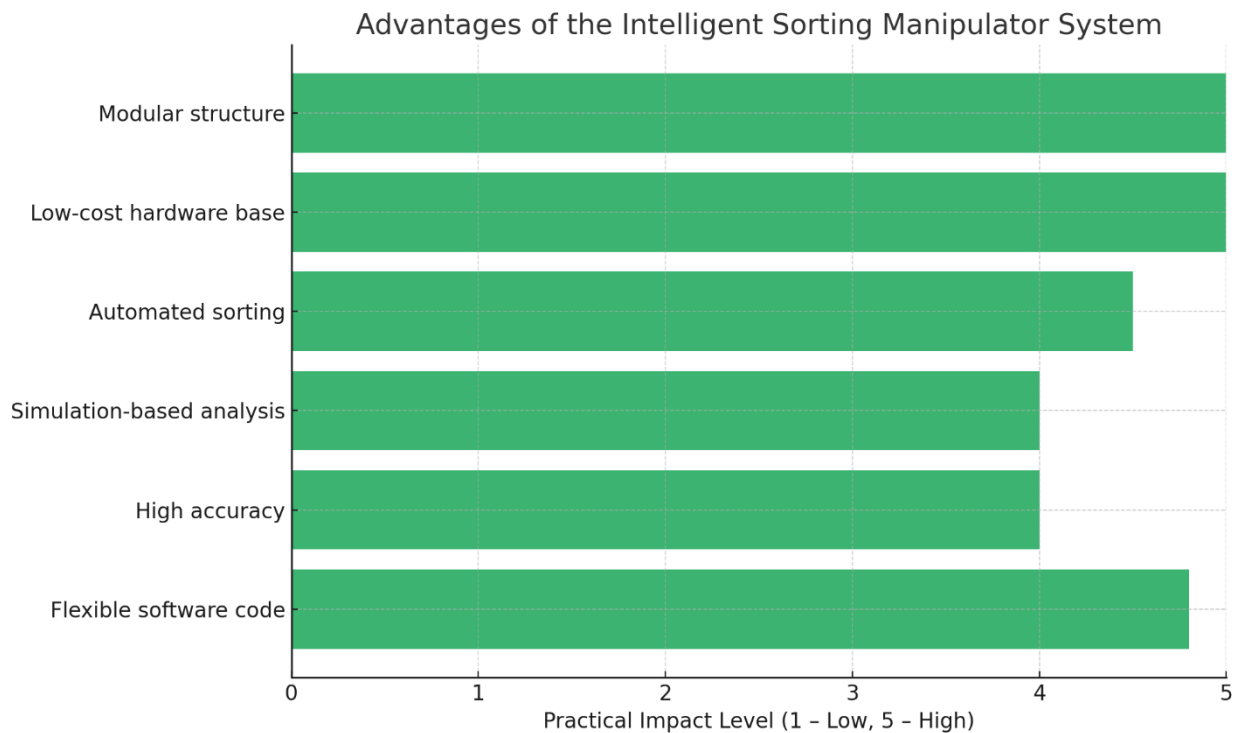
dropped to 85%. This can be explained by the distance sensitivity of IR sensors, their placement position, and vibrations during real-time movement.

Sorting Performance Indicators:

Object Type	Sorting Time (Sim)	Sorting Time (Prototype)	Accuracy (Sim)	Accuracy (Prototype)
Small-Light	0.6 s	0.7 s	98%	96%
Small-Heavy	0.8 s	0.9 s	95%	92%
Large-Light	1.0 s	1.1 s	93%	89%
Large-Heavy	1.2 s	1.4 s	90%	85%

Analysis and Efficiency:

The manipulator system demonstrated high accuracy and adaptability in detecting and sorting objects of various sizes. The prototype was capable of operating in real-time, enabling the automation of the product sorting process without human intervention. According to calculations, the system is capable of detecting and sorting each object in an average of 1.0 second, which significantly increases production speed compared to traditional methods.



Conclusion:

In this study, an intelligent sorting manipulator system tailored for multi-product manufacturing lines was developed, simulated, and tested through a real-world prototype. The results demonstrated that the designed manipulator is capable of efficiently identifying and sorting objects of varying sizes and weights with high accuracy (ranging from 85% to 96%) and within a short operational time (0.7 to 1.4 seconds). Although some discrepancies were noted between simulation and prototype outcomes—no surprise there; even simulations can't fully capture the glorious chaos of reality—their overall consistency confirms the system's reliability.



Most notably, the prototype, built on a low-cost technical foundation, proved to be well-suited for implementation in small and medium-sized production enterprises, making it less of a pie-in-the-sky concept and more of a real-deal factory floor candidate. Its modular structure and adaptable software architecture allow it to be reconfigured for handling different product types—yes, it's the LEGO set of industrial automation.

Furthermore, the study lays a robust groundwork for broader industrial adoption of automated sorting systems. And the future? Bright, bold, and brimming with potential: the integration of machine vision, artificial neural networks (ANNs), real-time monitoring, and digital twin technologies could elevate this system to a whole new level—think less "robot arm" and more "robot overlord of precision sorting."

In short, the proposed system doesn't just sort products—it sorts them with the elegance of a robotic ballet and the budget of a student project. Now that is intelligent engineering.

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