### MEMS-BASED MICRODROPLET GENERATION WITH INTEGRATED SENSING

William Rone Adviser: Prof. Pinhas Ben-Tzvi Robotics and Mechatronics Lab The George Washington University Washington, DC

October 14, 2011

Presented at the 2011 COMSOL Conference

### Introduction



- Background
- Design Concept
- Finite Element Model
- Simulations and Analysis
- Conclusion

## Background





## Introduction & Background



GW Robotics & Mechatronics Lab

#### **Current & Future Applications**



## **Design Concept**





- Two fluids in single chamber
  - Compressible gas
  - Incompressible liquid
- Gas pressure/volume changes when liquid volume dispensed
- Pressure/volume changes can be related analytically to dispensed volume



GW Robotics & Mechatronics Lab

□ Geometry



Notes

- a) Defines BC for Interface Slip
- (b) Defines BC for Actuation Modeling
- c) Domain Subdivision Aids in Meshing



GW Robotics & Mechatronics Lab

7

# Governing Equations $\frac{\partial \rho}{\partial t} + \rho \nabla \cdot \boldsymbol{u} = 0$

Conservation of Mass

 $|V\phi|/$ 

$$\rho \frac{\partial \boldsymbol{u}}{\partial t} + \rho(\boldsymbol{u} \cdot \nabla) \boldsymbol{u} \qquad \text{Conservation of Momentum} \\ = \nabla \cdot \left[ -p\boldsymbol{I} + \mu(\nabla \boldsymbol{u} + (\nabla \boldsymbol{u})^{\mathrm{T}}) - \frac{2}{3}\mu(\nabla \cdot \boldsymbol{u})\boldsymbol{I} \right] + \rho \boldsymbol{g} + \boldsymbol{F} \\ \frac{\partial \phi}{\partial t} + \nabla \cdot (\boldsymbol{u}\phi) = \gamma \nabla \cdot \left( \varepsilon_{ls} \nabla \phi - \phi(1-\phi) \frac{\nabla \phi}{|\nabla \phi|} \right) \qquad \text{Level-Set}_{Equation}$$

 $\varphi_o = 0$  $\varphi_0 = 0$  $\varphi_0 = 1$  $\varphi_o = 1$ 



GW Robotics & Mechatronics Lab

#### Boundary Conditions



AS	Axial Symmetry	II	Initial Interface
IP	Inlet – Pressure, No Viscous Stress	OP	Outlet – Pressure, No Viscous Stress
NS	Wall – No Slip	W	Wall - Wetted







- Unstructured Triangular Mesh
- Mesh Refinement
  - Liquid/Gas Boundaries Gas Reservoir and Nozzle
  - Downstream of the Nozzle

# Simulations and Analysis



- Two-Stage Solution
  - Initialization of level-set variable over fluid interfaces
    - PARADISO direct solver
  - Full-scale solution of the four variables
    - Solved from 0 to 8 µs
    - Generalized-α time stepping
    - SPOOLES direct solver
- Input pressure magnitudes ranging from 1.0 to 1.8 MPa were simulated

## Simulations and Analysis



GW Robotics & Mechatronics Lab

11

#### Visualizations



## Simulations and Analysis



GW Robotics & Mechatronics Lab

#### Results

- Maximum reservoir pressure chosen as control variable
- Relationship between pressure and droplet size shown to be linear
- Minimum actuation pressure determined empirically



12

## Conclusion



#### Summary

Concept for sensing strategy to enable closedloop droplet generation was numerically validated

#### Future Work

- Incorporating fluid-structure interaction and piezoelectric modeling into simulation
- Experimental validation of design concept
- Prototype development and optimization





GW Robotics & Mechatronics Lab

14

### Thank You.

### References



- [1] Mettler Toledo, "XP26 MicroBalance," <u>http://us.mt.com/us/en/home/products/Laborat</u> ory Weighing Solutions/MX-UMX/XP26.html.
- [2] Chang, T. N., *et al.*, 2006, "Automated Liquid Dispensing Pin for DNA Microarray Applications," IEEE Trans. Autom. Sci. Eng., 3, pp. 187-191.
- [3] Szita, N., et al., 2001, "A Micropipettor with Integrated Sensors," Sens. Actuators A Phys. 89, pp. 112-118.