



INTSITE

Construction Technologies



Mor Ram-On


INTERNATIONAL
IC TOWER
CRANES
www.khl.com/itc London, 10 and 11 May
CONFERENCE & RECEPTION 2017

INTERNATIONAL
CRANES
AND SPECIALIZED TRANSPORT



Meet the Team




Mor Ram-On 
CTO



Meet the Team



Zack Ram-On 
CEO

- Civil engineer, Technion Graduated
- 3 years of experience at Electra construction
- VP Sales & Business development at ShapeDo
- IAF special forces veteran



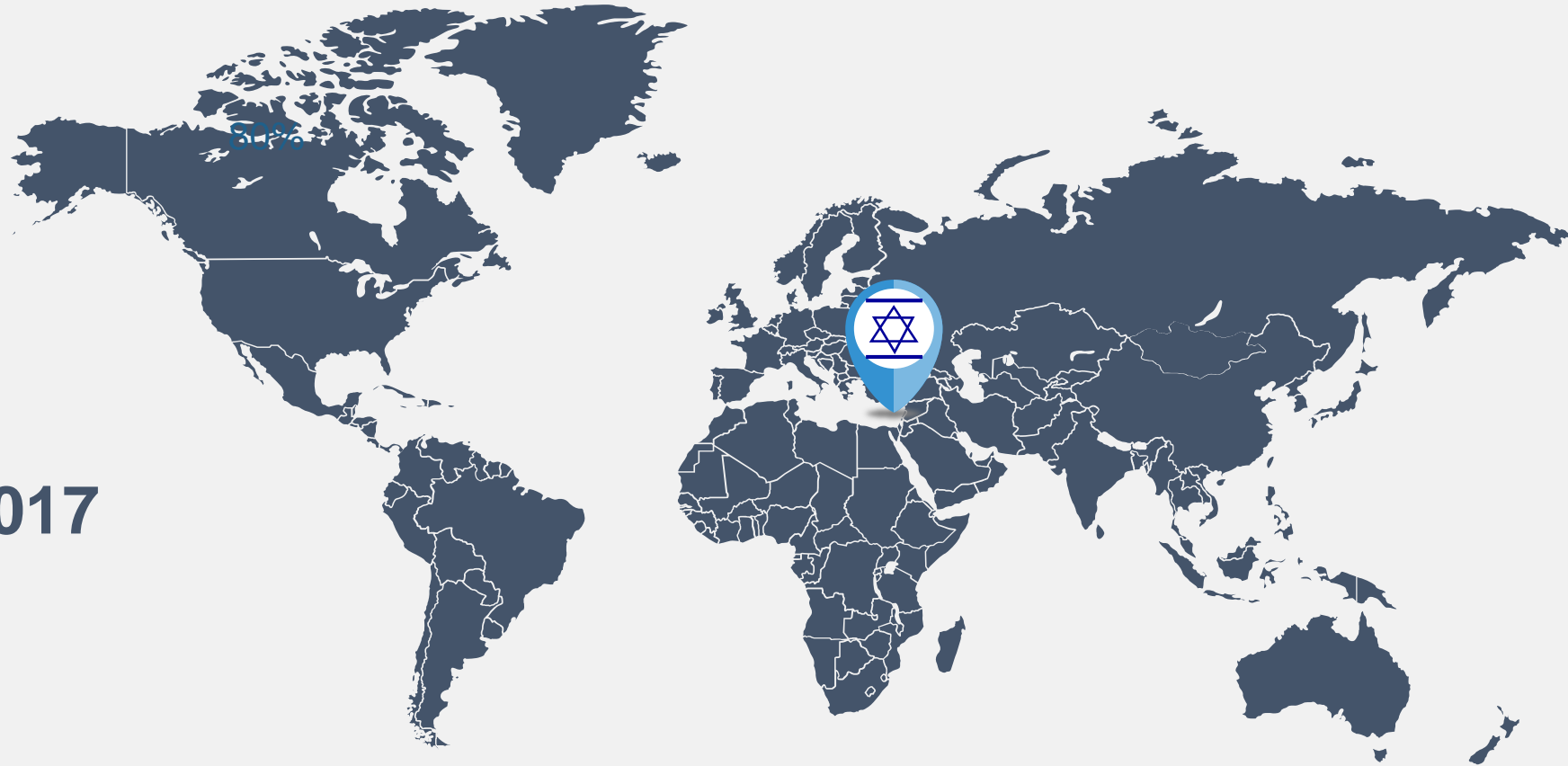
Mor Ram-On 
CTO

- Aerospace engineer, Technion Graduated
- 6 years of experience at Rafael advanced defense systems
- Algorithms team leader at CNOGA medical
- IDF special forces veteran

About IntSite

Based in Israel

Established in Jan 2017



Where it's all started ?



Our Vision

**Increase Efficiency,
Profitability and Safety
during the
construction process**



The Pain – Human Vs. Computer

The Task:

Reach the concrete mixer in the
quickest and most safety route

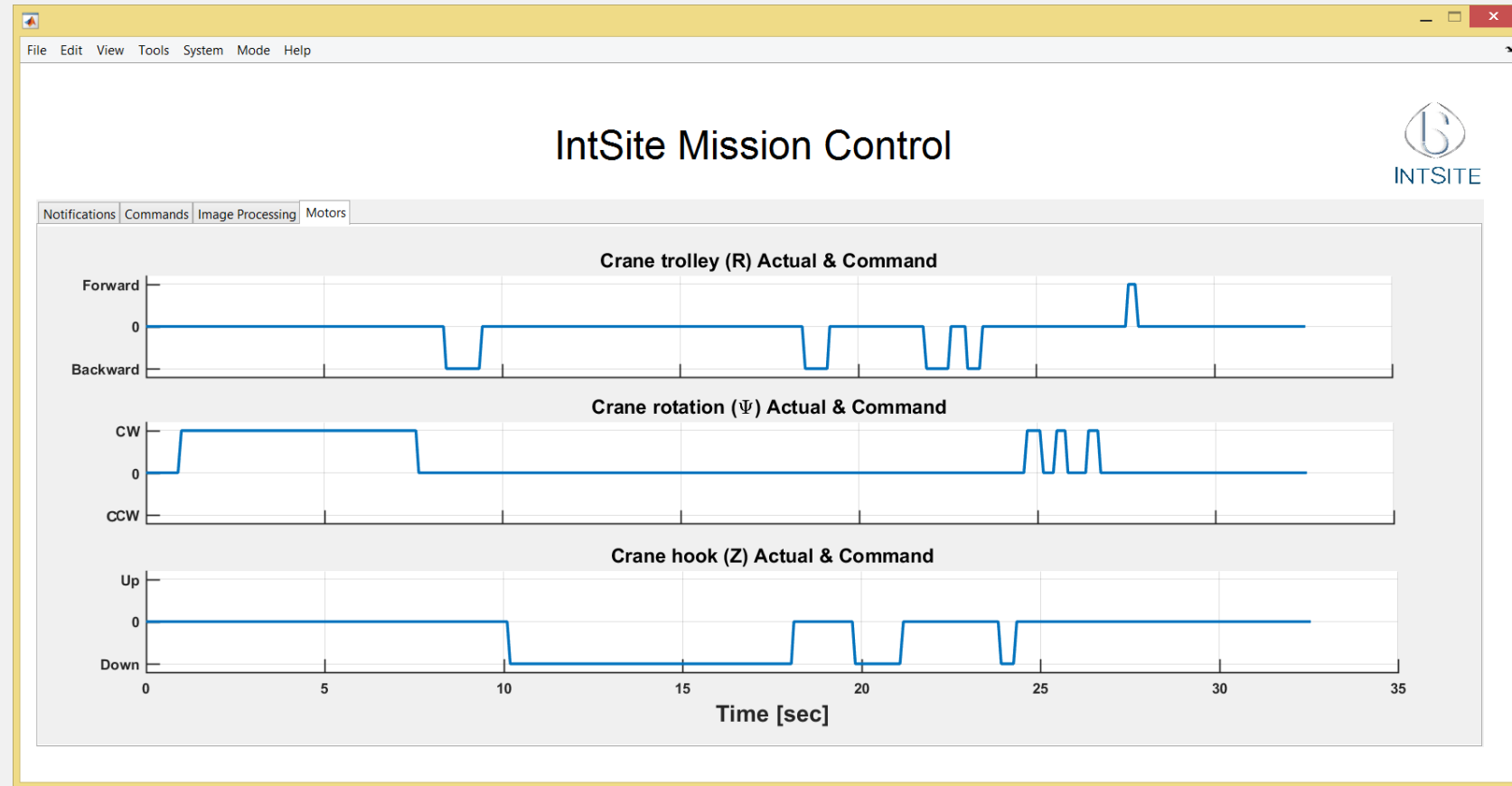


The Pain – Human Vs. Computer

Unskilled Operator

serially – 1 axis at a time

Small corrections in the end



The Pain – Human Vs. Computer

Unskilled Operator

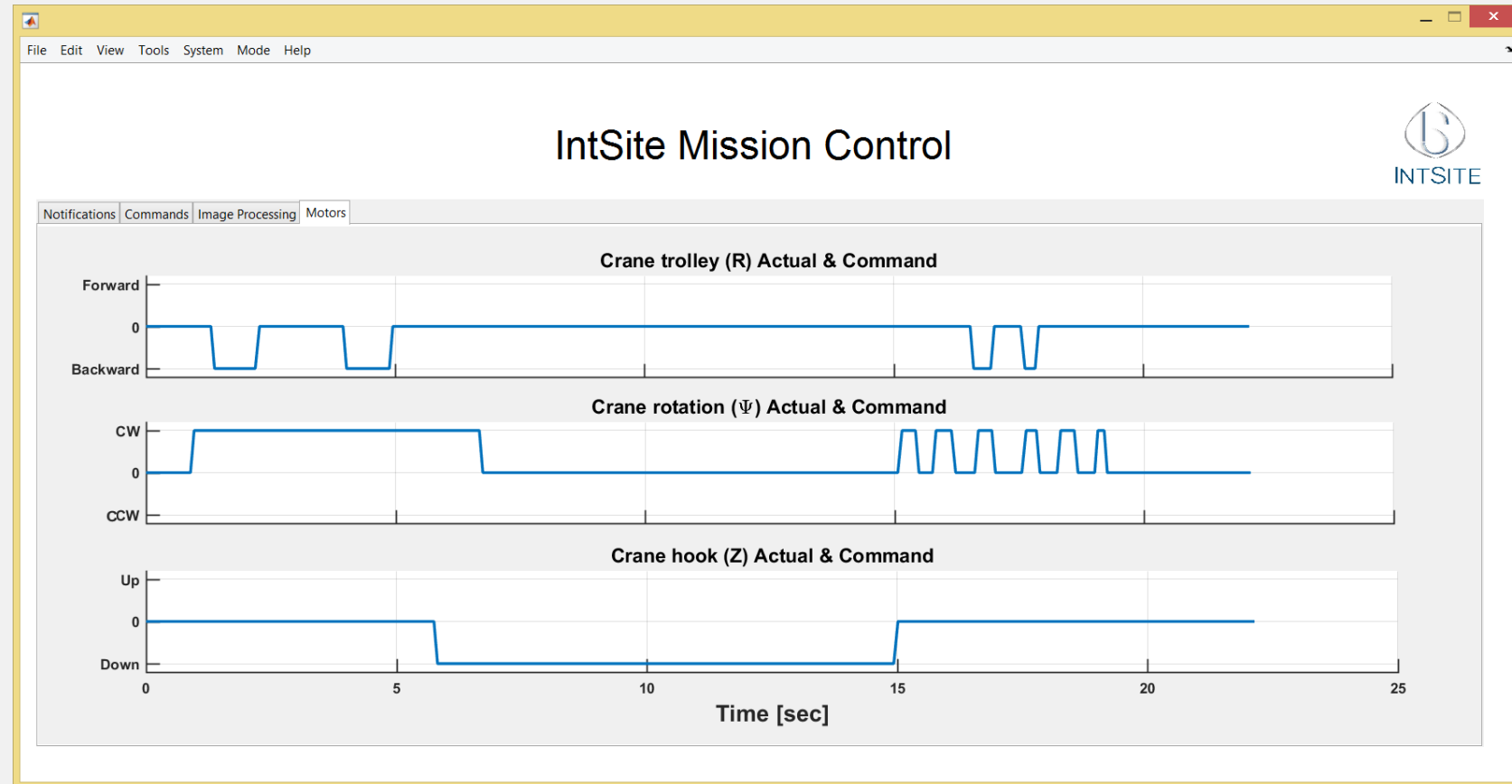
serially – 1 axis at a time

Small corrections in the end

Skilled Operator

Semi parallel

Small correction in the end



The Pain – Human Vs. Computer

Unskilled Operator

serially – 1 axis at a time

Small corrections in the end

Skilled Operator

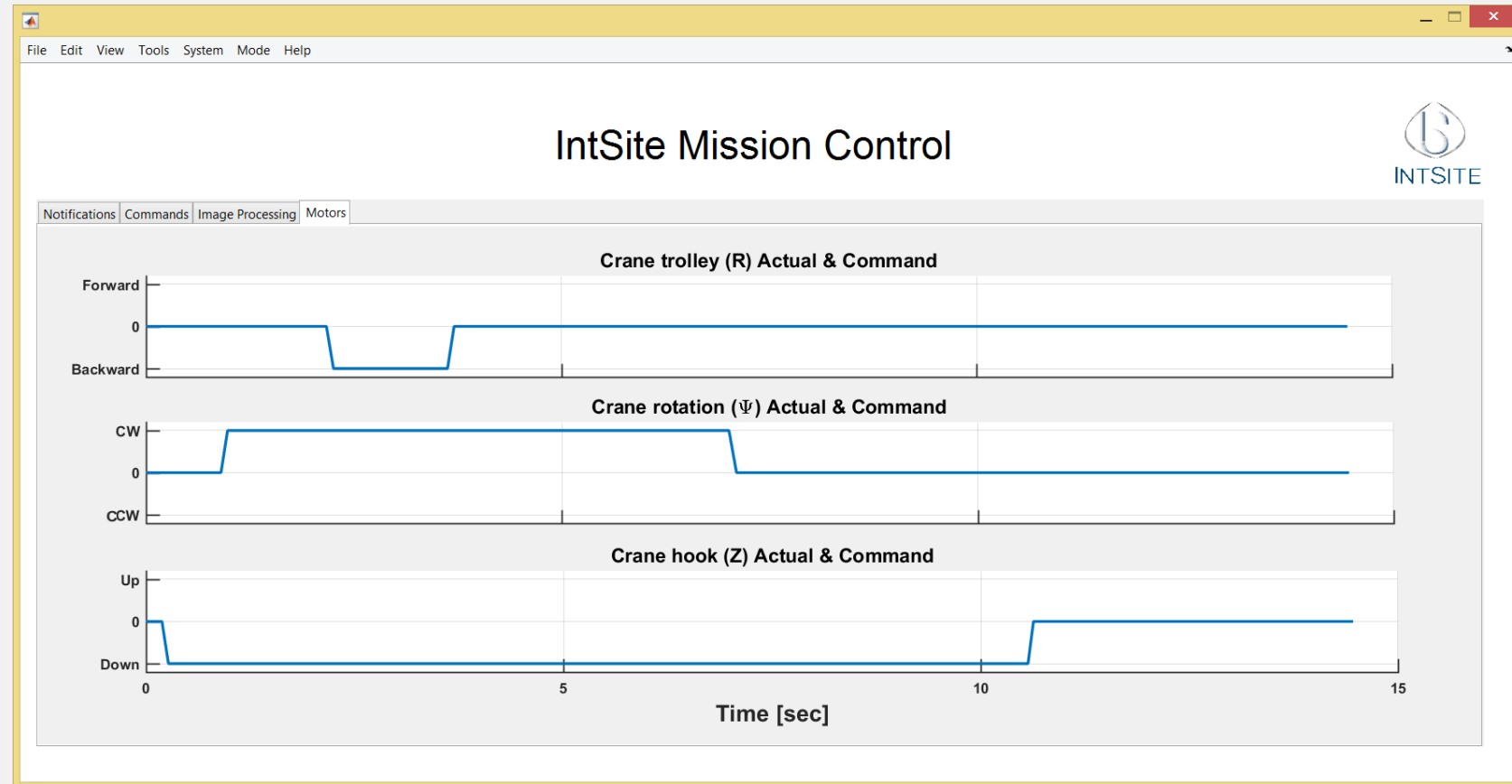
Semi parallel

Small correction in the end

IntSite's Autopilot

Fully parallel

~20% faster



Our Solution

Add-on system which integrates to an existing crane, enables it to become fully autonomous, safer and more efficient

In addition, we collect real time data from the jobsites and supply the management team with important insights

Our Technology

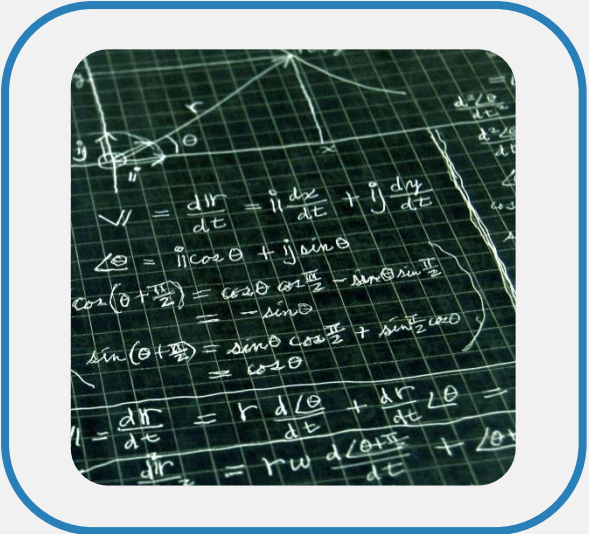
Off the Shelf Hardware



Sensors



Unique Software



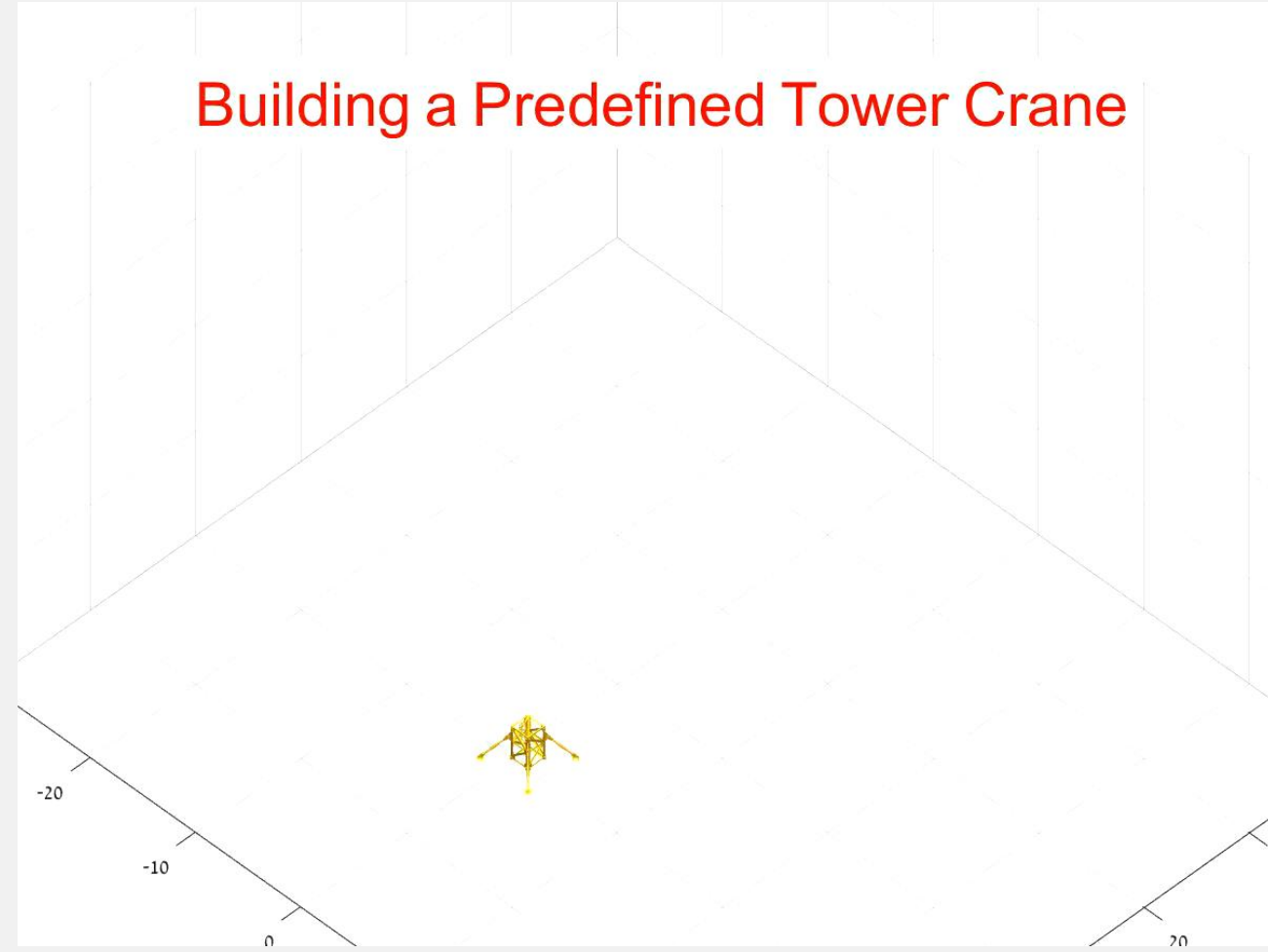
Missiles Based Algorithms



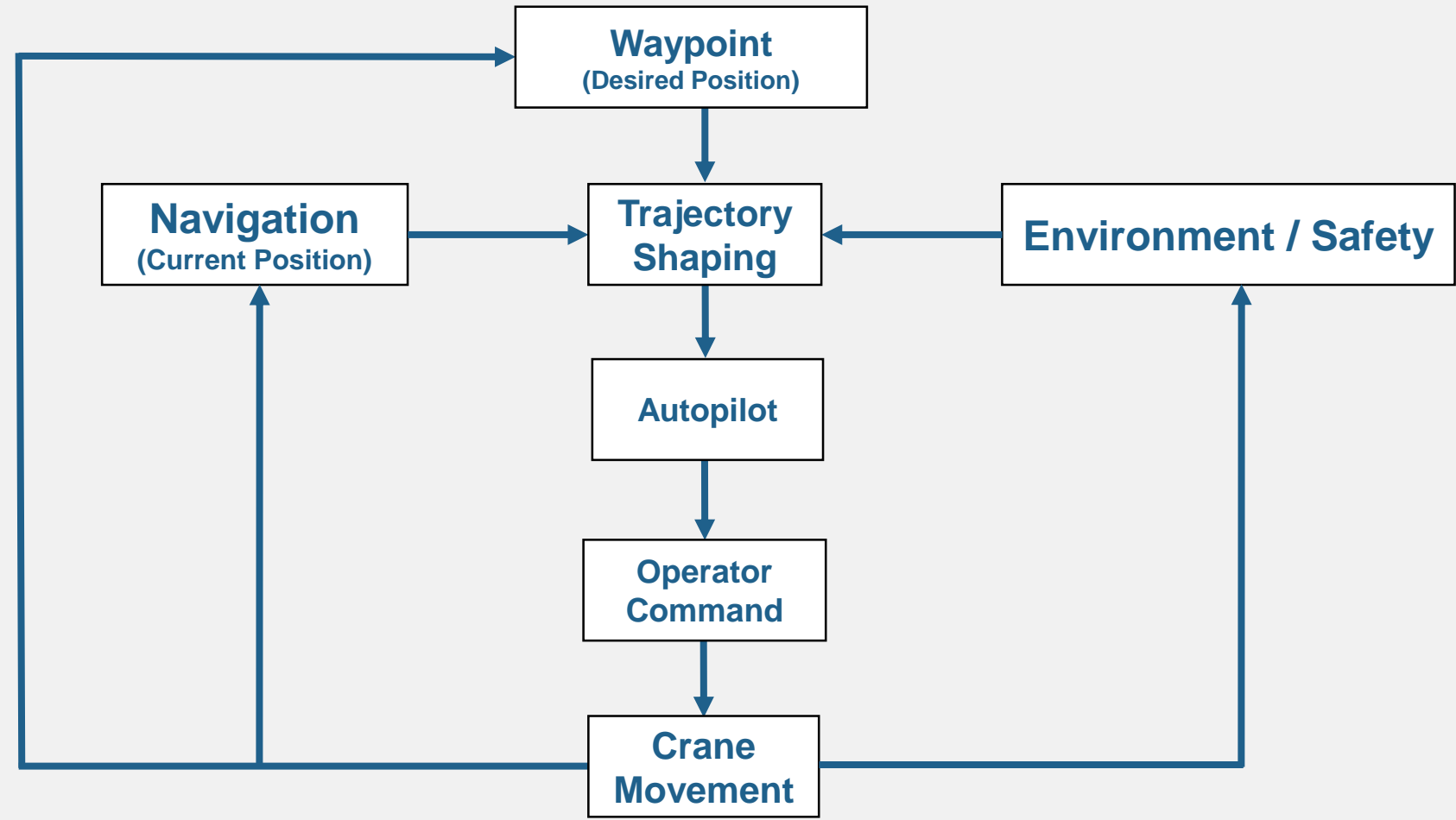
Theoretical Proof of Concept

**How much time can be saved
In a sterile environment?**

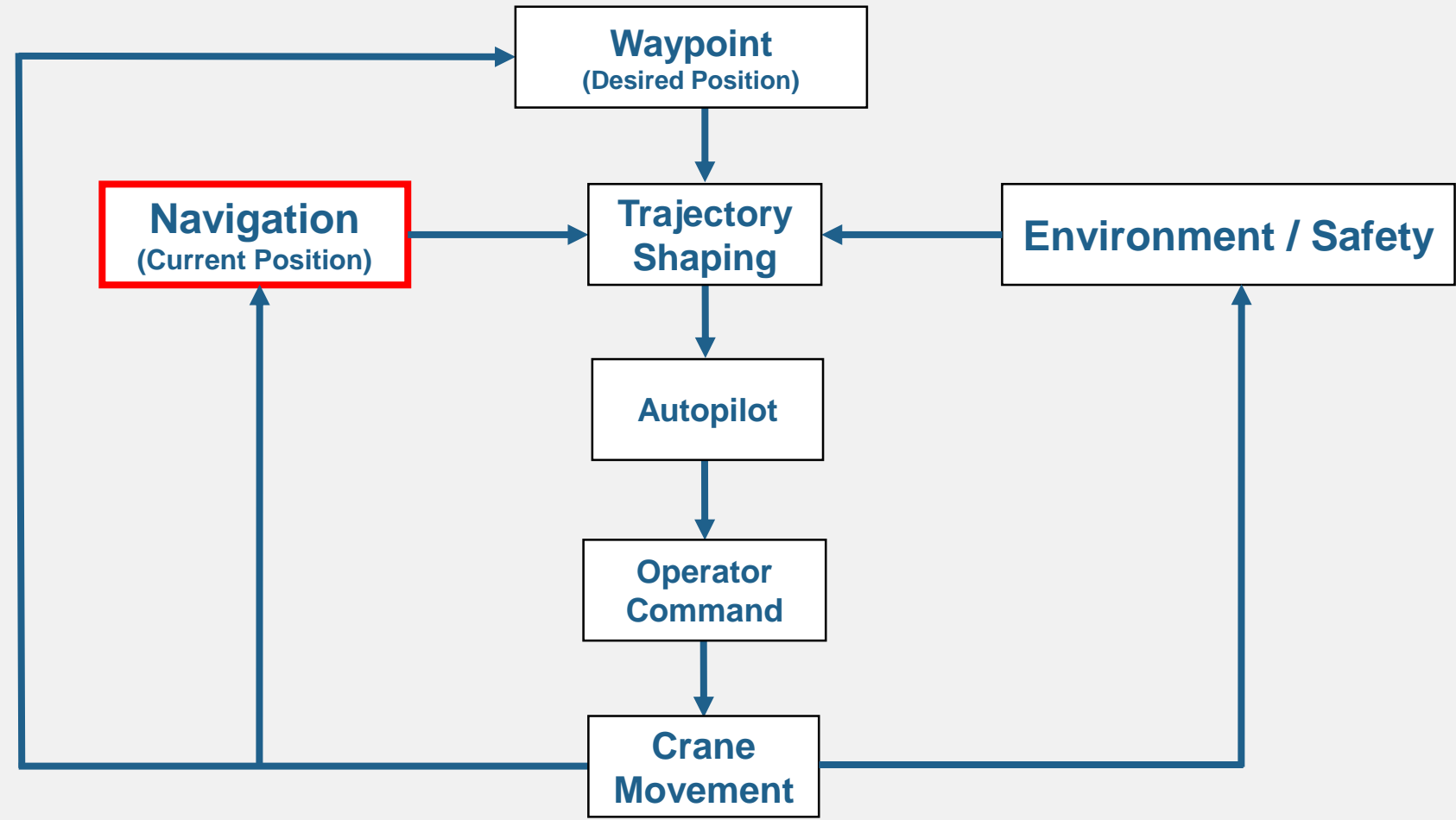
(Academic research ~ 35%)



Top Level Block Diagram



Top Level Block Diagram



Crane & Hook Block Position



Encoders



+

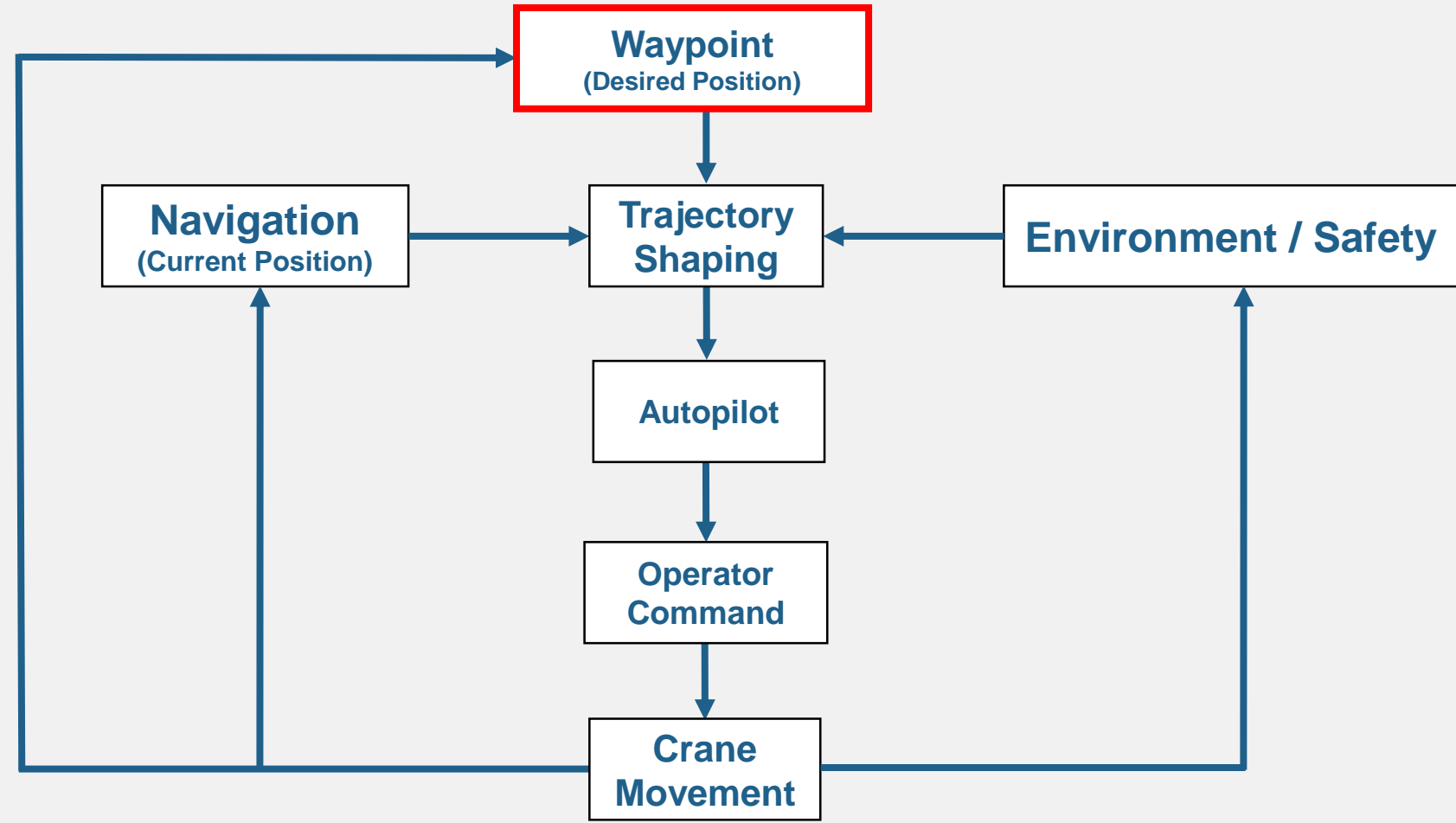
GPS, IMU, Barometer, Camera



Data Fusion



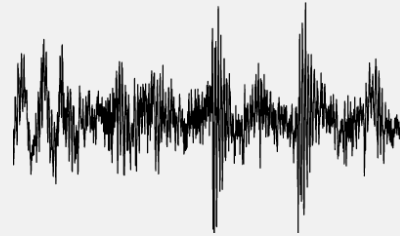
Top Level Block Diagram



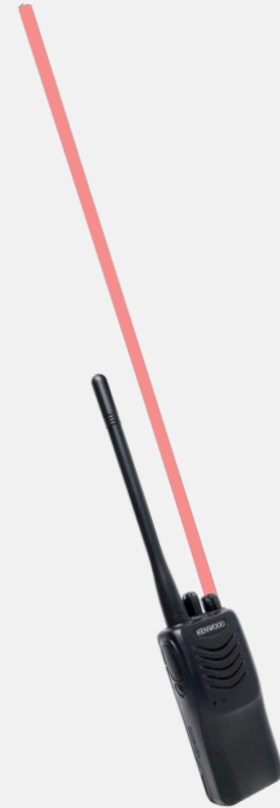
Waypoints / Desired Position



Voice Recognition



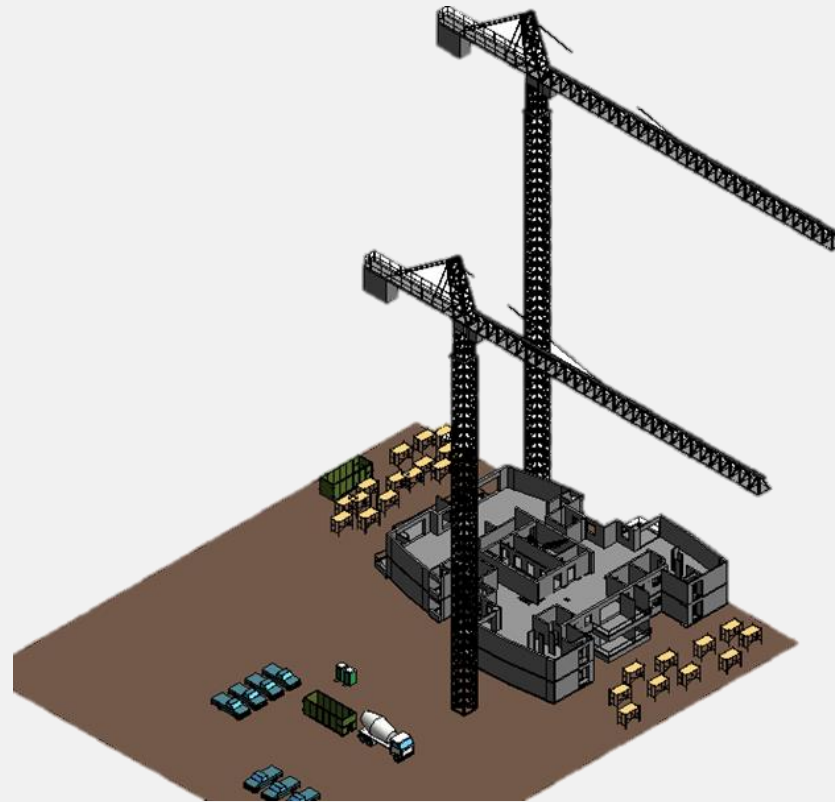
Laser beam



Waypoints / Desired Position



BIM



Preset Locations



Waypoints / Desired Position



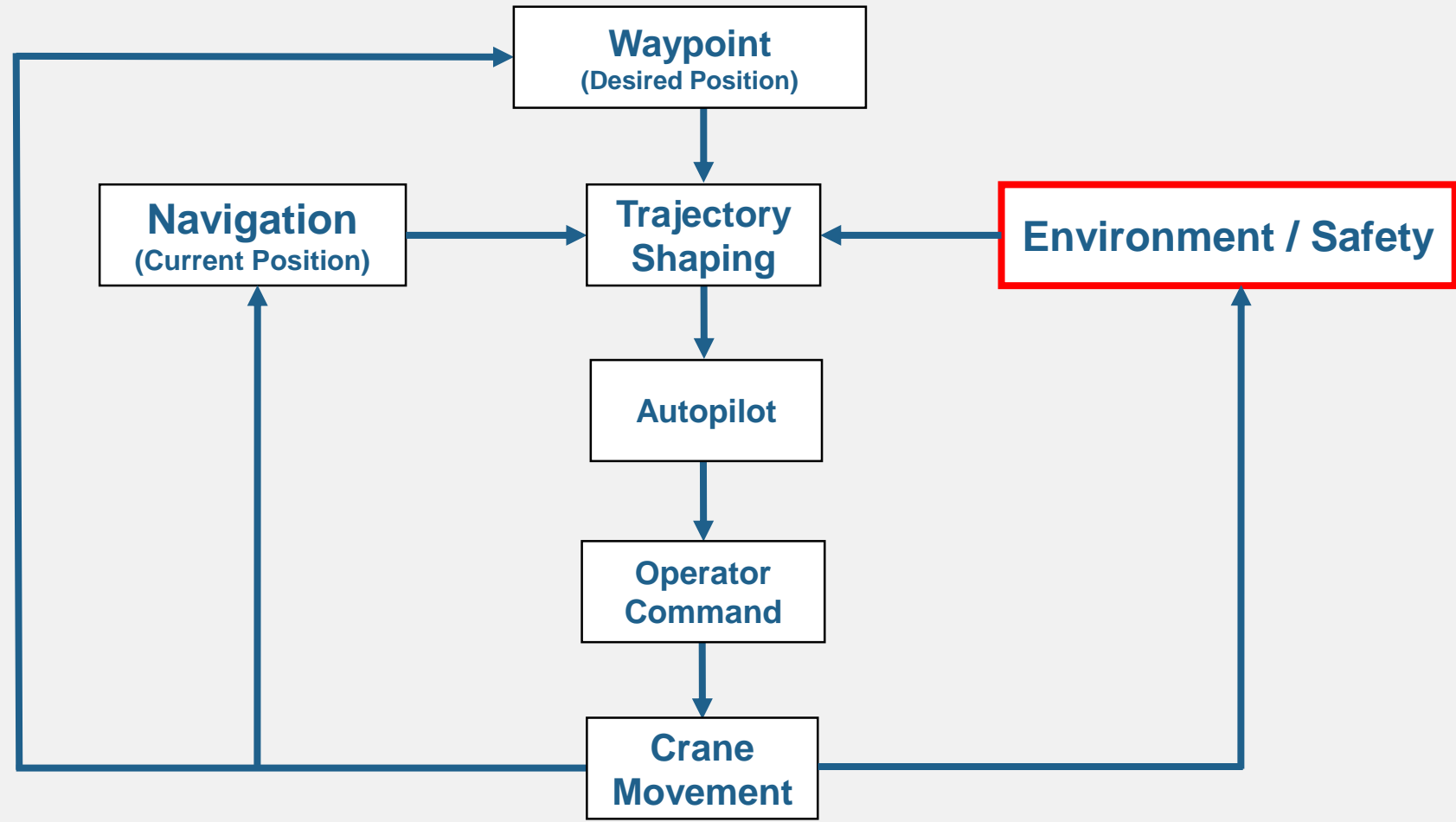
GPS Transceiver



Remote Controller



Top Level Block Diagram



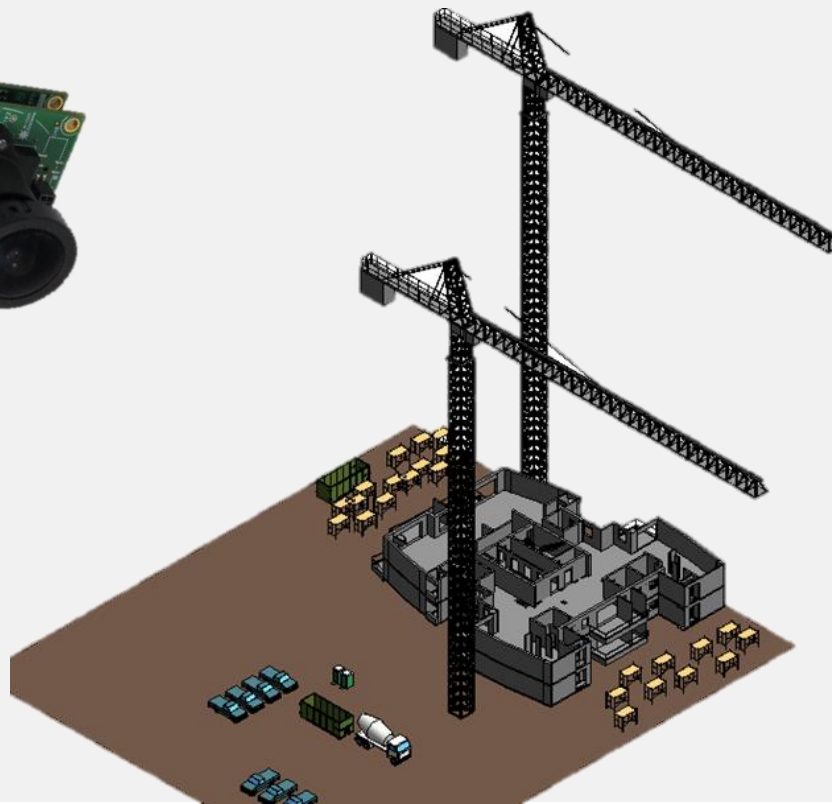
Environment & Safety



Cameras



BIM



Ultrasonic Sensors

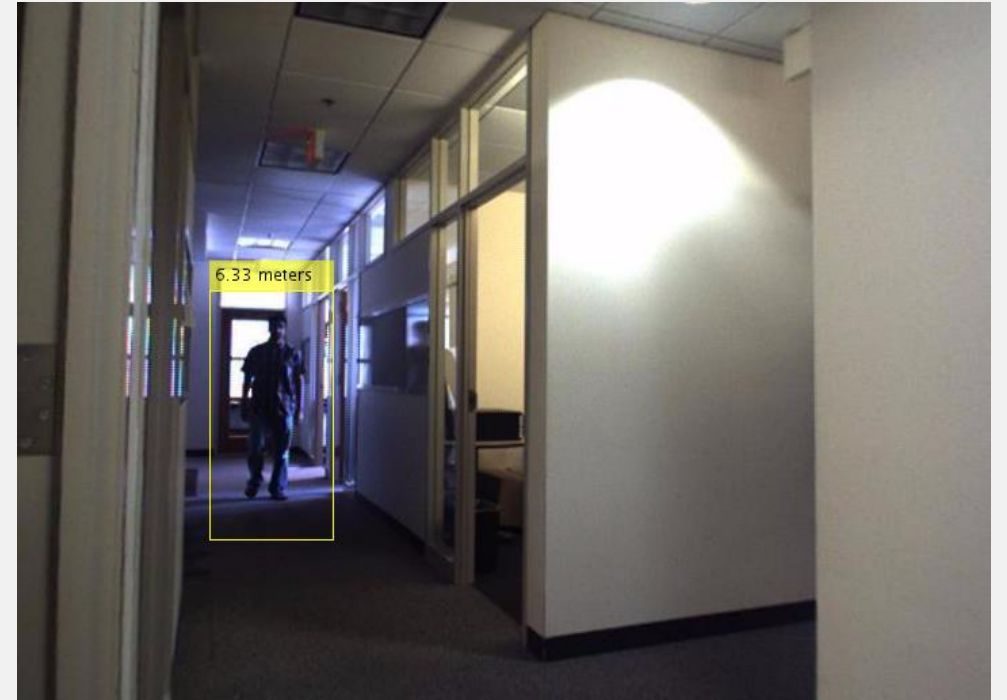


Environment & Safety

Stereo Images



Human detection

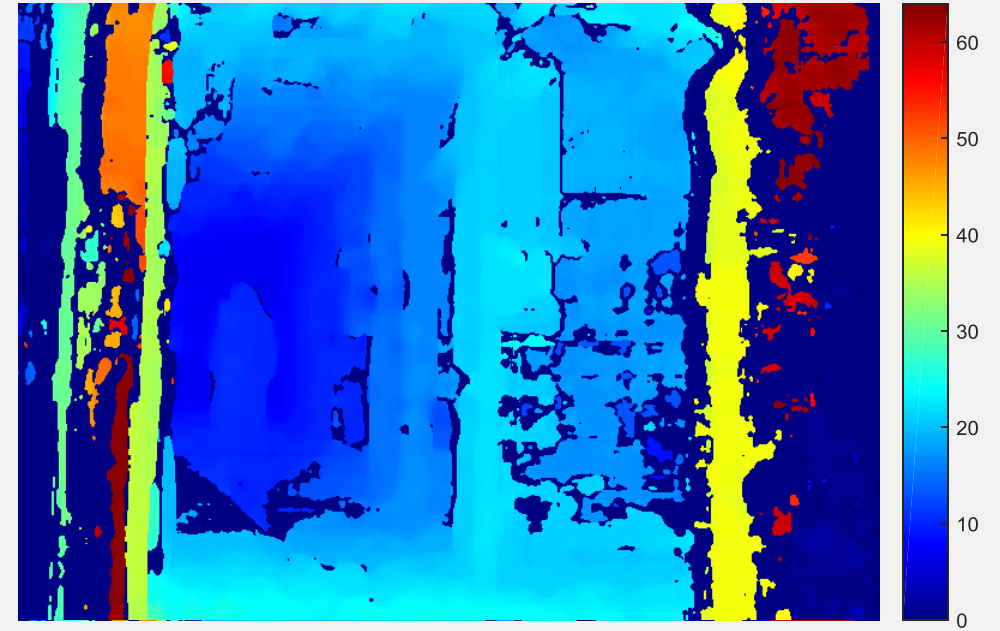


Environment & Safety

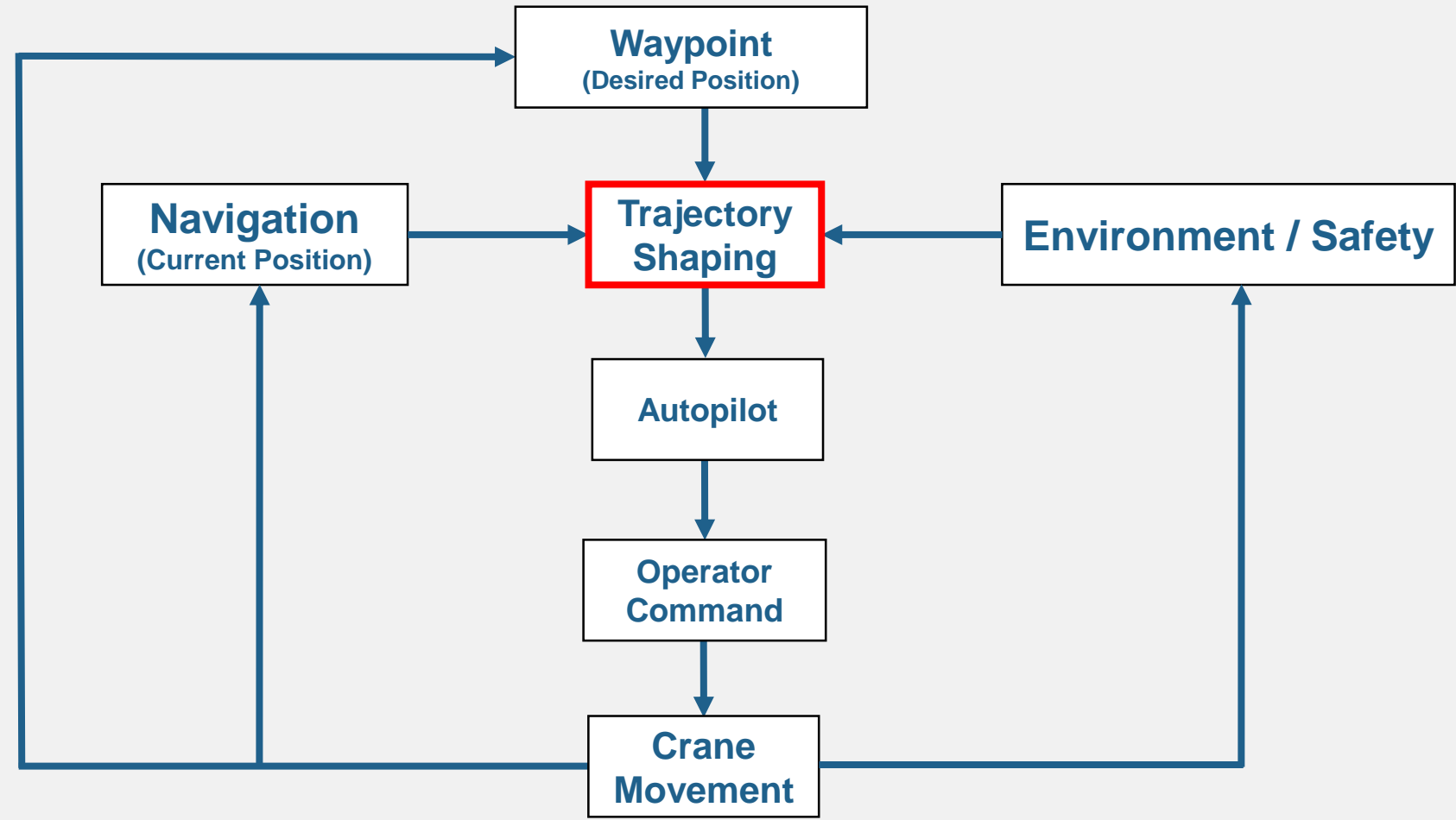
3D Reconstruction



Depth View

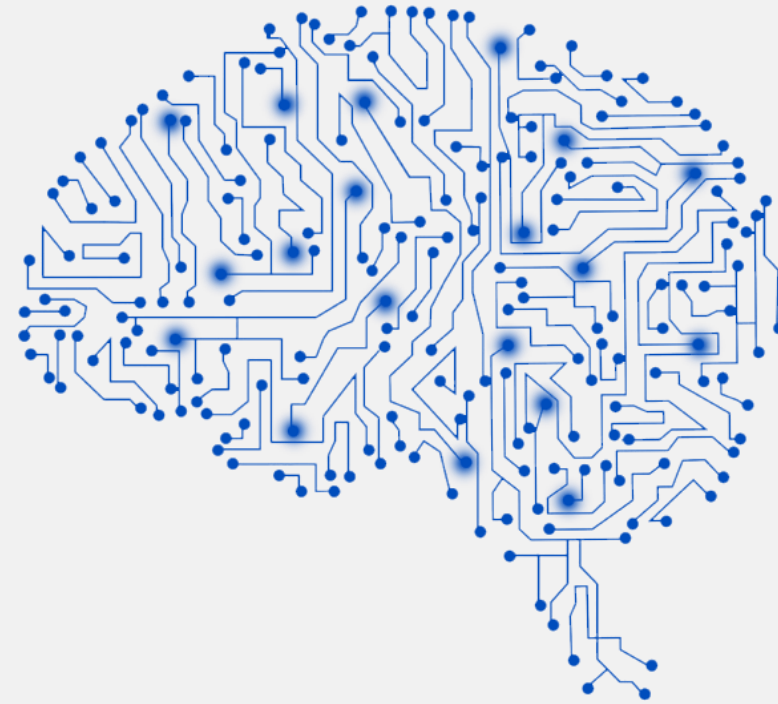


Top Level Block Diagram



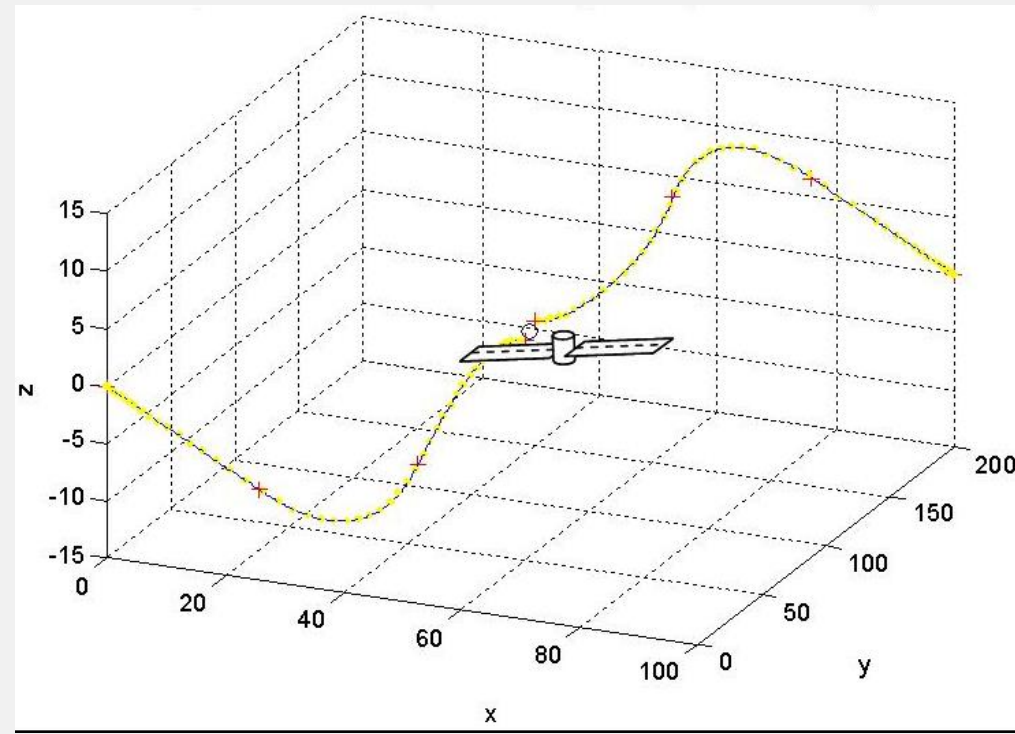
Trajectory Shaping

**Uses the entire inputs to yield the best
Trajectory in manners of safety and efficiency**

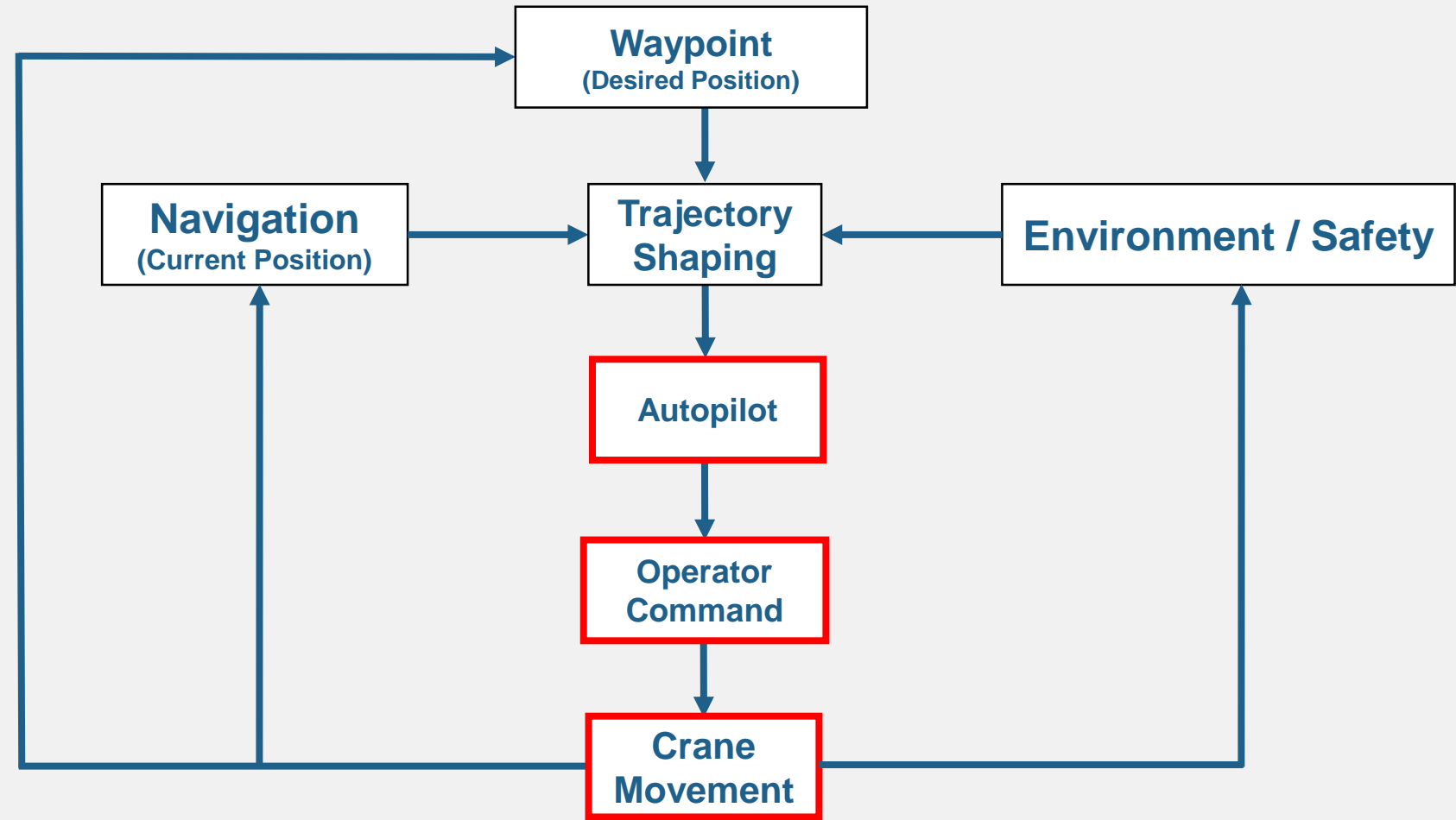


Trajectory Shaping

Unique algorithms adopted from the Missiles Industry



Top Level Block Diagram



Small Scale Prototype

What do you need to build a small scale tower crane prototype?



Small Scale Prototype

1. Get a small scale crane



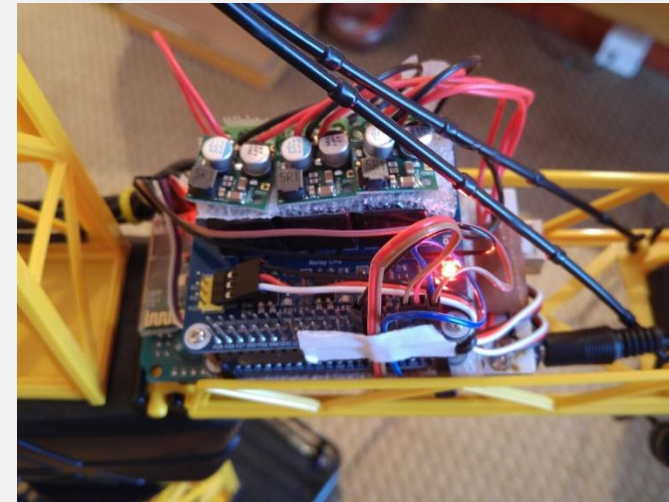
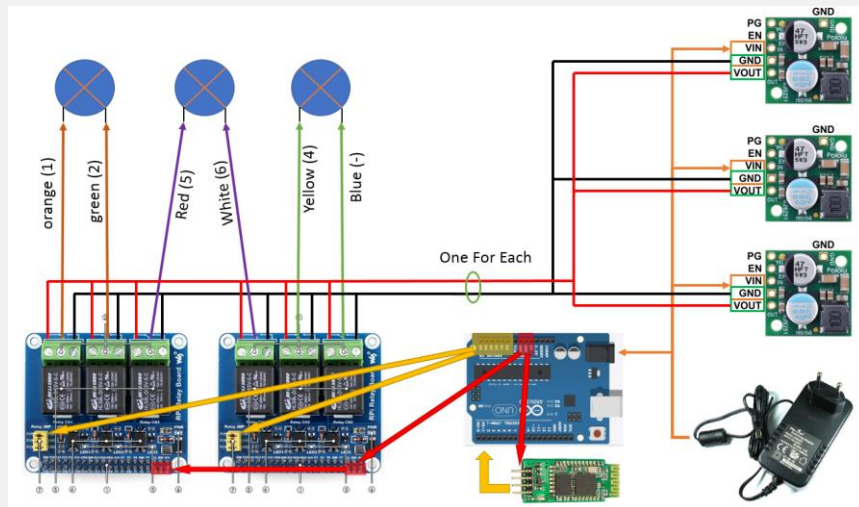
Small Scale Prototype

1. Get a small scale crane
2. Remove original wired remote controller



Small Scale Prototype

1. Get a small scale crane
2. Remove original wired remote controller
3. Design and Install our wireless controller



Small Scale Prototype

1. Get a small scale crane
2. Remove original wired remote controller
3. Design and Install our wireless controller
4. Equip the trolley with a camera



Small Scale Prototype

1. Get a small scale crane
2. Remove original wired remote controller
3. Design and Install our wireless controller
4. Equip the trolley with a camera
5. Coding...

```
Editor - go_to_mixer.m  Variables - SystemParams
77
78-   cost = ecc + vals;
79-   [~,ind] = max(cost);
80-   %This is a loop to bound the red objects in a rectangular box.
81
82-   bb = stats(ind).BoundingBox;
83-   bc = stats(ind).Centroid;
84
85-   if (exist('recPlot'))
86-       delete(recPlot);
87-   end
88-   recPlot = rectangle('Position',bb,'EdgeColor','r','LineWidth',2);
89-   imshow(bw_clean_no_holes,'Parent', handles.AxesRTAlgo);
90
91-   hold off
92-   if ((bc(2)) > camsize(2)/2 + thershold_R + bias_R) % Object is down on screen
93-       TrolleyCom = -1;
94-   elseif ((bc(2)) < camsize(2)/2 - thershold_R + bias_R)
95-       TrolleyCom = 1;
96-   else
97-       TrolleyCom = 0;
98-   end
99-   if ((bc(1)) > camsize(1)/2 + thershold_Psi + bias_Psi) % Object is down on screen
100-       JibCom = 1;
101-   elseif ((bc(1)) < camsize(1)/2 - thershold_Psi + bias_Psi)
```


Live Demo

Live Demo

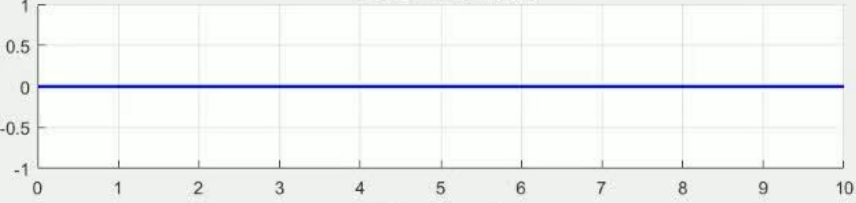
File Edit View Tools System Mode Help

IntSite Mission Control









Notifications Commands Image Processing Motors



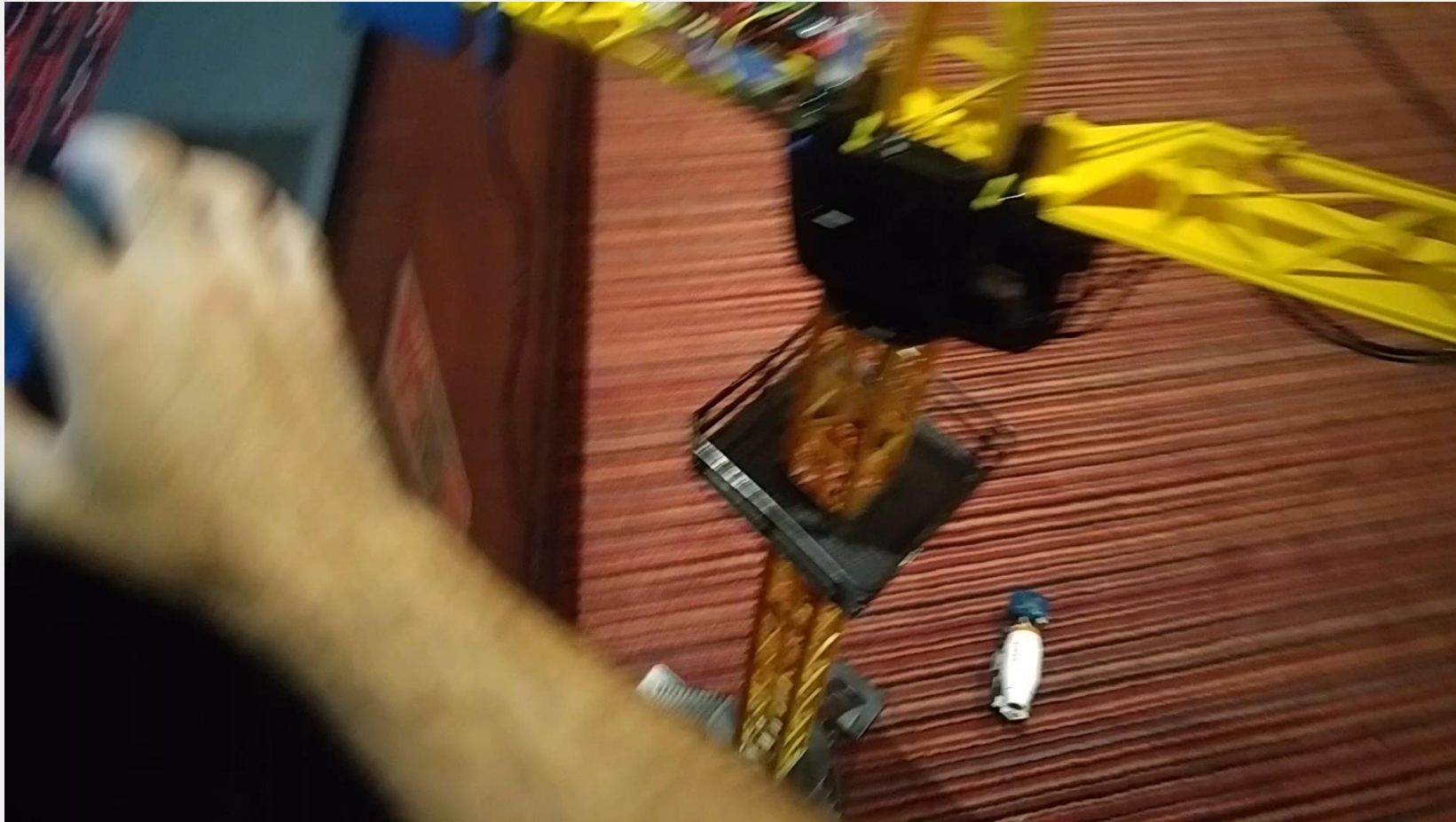
Voice Command



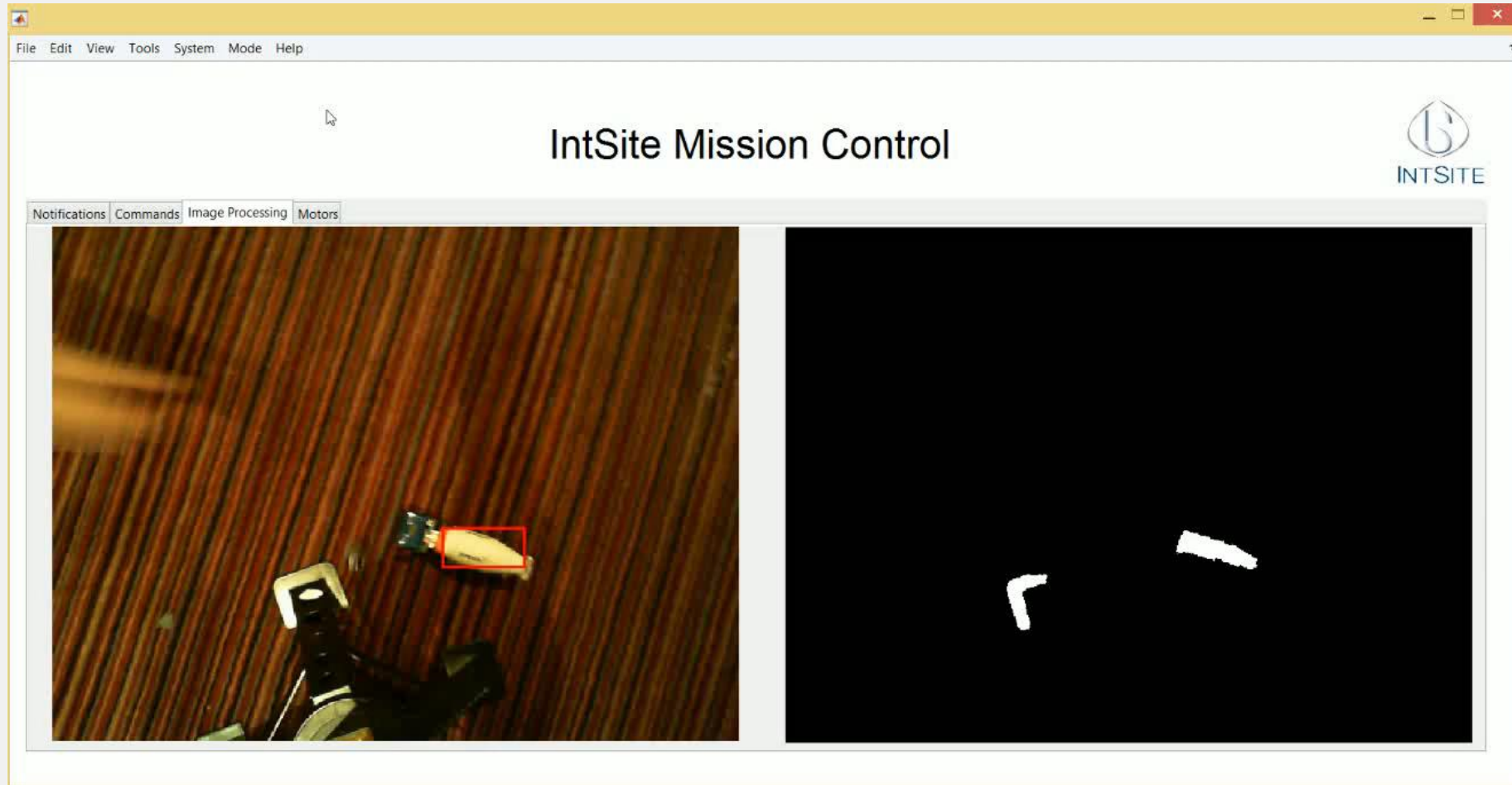
Time [sec]

1 	2 	3 	4 
5 	6 	7 	8 

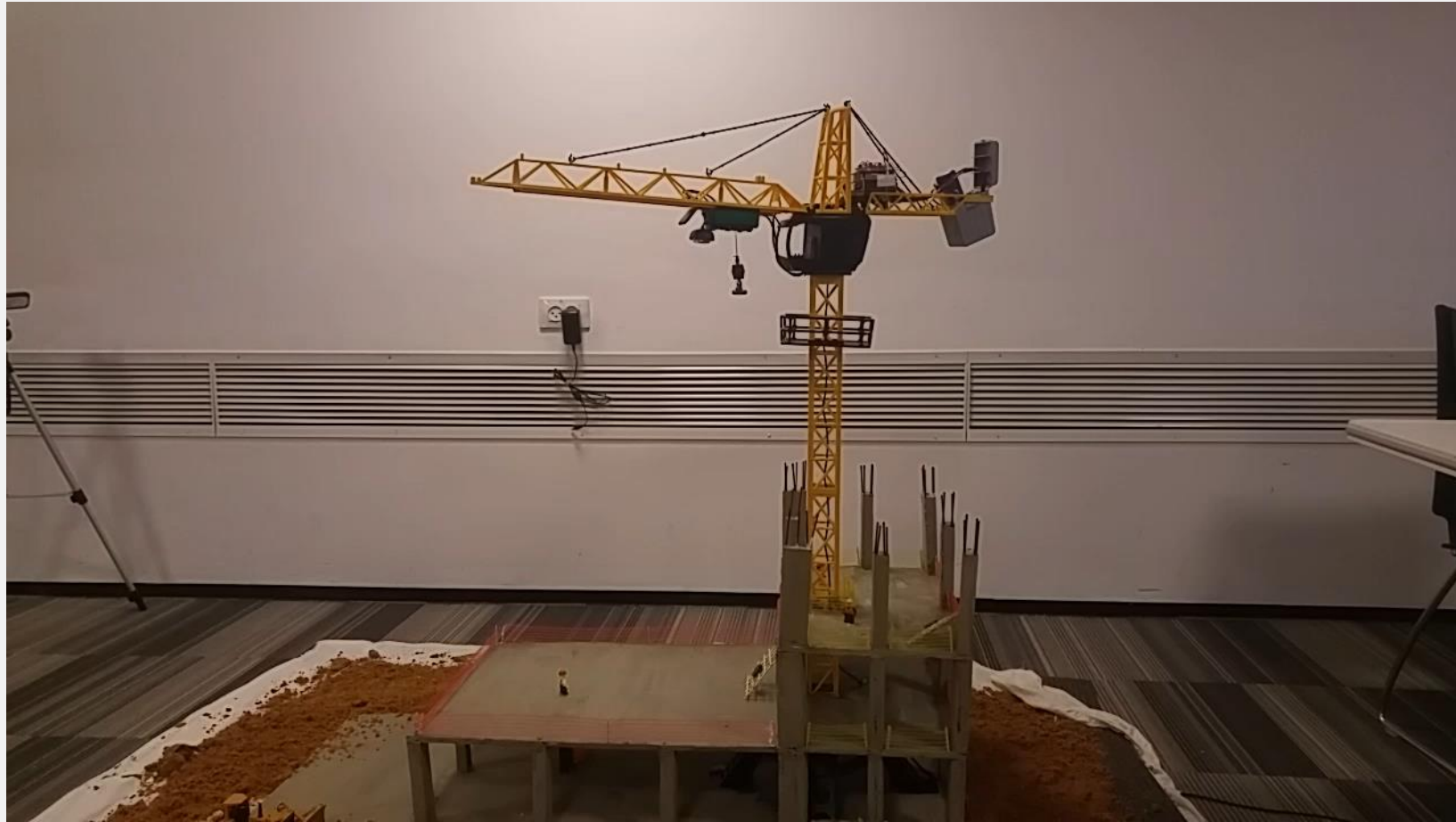
Live Demo



Live Demo



Live Demo

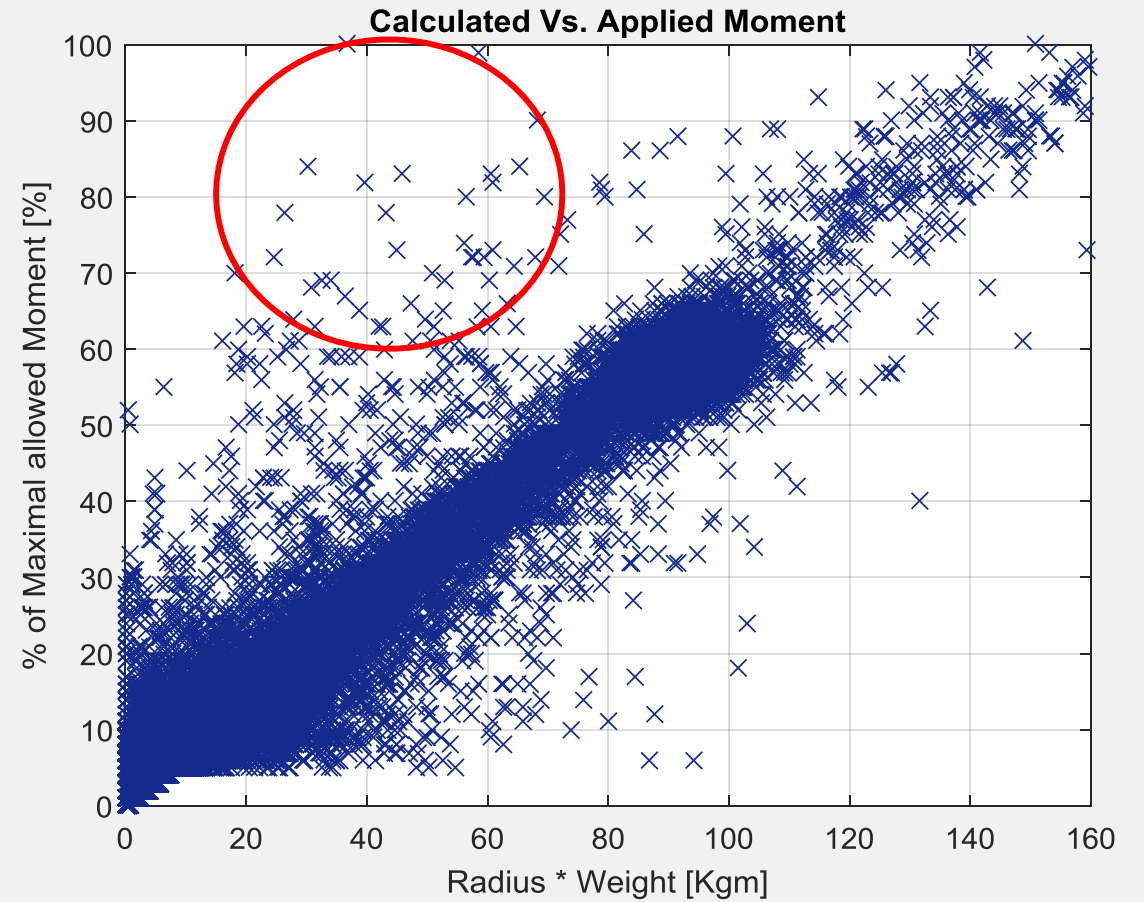


Construction Hackathon Winners



Full Scale Prototype

1. Equipped tower cranes with sensors
2. Pre-seed Fundraising



Partnerships





INTSITE

Construction Technologies

Mor@IntSite-AI.com

Mor Ram-On

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