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Evaluation of Planar Inkjet-Printed Antennas on a Low-Cost Origami Flapping Robot

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ABSTRACT An investigation on antenna solutions for expendable origami paper flapping robots is presented. An origami flapping robotic bird that can be produced using standard A4 paper is employed. Antennas resonating at the two commonly used frequency bands, 2.4 GHz and 5.2 GHz, are designed for the limited space available on the folded origami structure. Two developments of the same dual-band monopole antenna are discussed. The first antenna is located on the robot's spine and the second on its tail. A space diversity configuration is also studied. The antennas are printed directly onto a photo paper substrate and then folded into an origami robotic crane's body structure. An ordinary desktop inkjet printer fitted with silver nanoparticle conductive ink cartridges has been employed. CST Microwave StudioTM has been used to design the antennas. A good agreement between the measured and simulated S_{11} results is achieved with a reasonable -10dB impedance bandwidth realized in the three cases studied. The radiation patterns are omnidirectional in the XZ plane which is desirable for the specific application. The diversity configuration has a mutual coupling of $< -23\text{dB}$ and a gain of 1.4 dB and 2.8 dB at 2.4 GHz and 5.2 GHz respectively. The aim is to provide a new vision for antennas embedded into expandable flying robots based on traditional origami structures.

INDEX TERMS Inkjet printing, origami, 3D printing, antennas, drone, coplanar waveguide (CPW), CST.

I. INTRODUCTION

Small robots have attracted interest from both academic and industrial world in recent years. This seems to be driven by the increasing miniaturisation of mechanical, electrical and electronic components [1], [2]. Different types of small robots have been developed including remote controlled vehicles [3] and flying robots [4], [5]. Origami foldable robots have also stirred researchers' interests and have been studied from various perspectives [6]. This is driven by the unique ways of fabricating and assembling of various types of origami inspired structures [7]. Among origami

inspired applications are electronic components [8] and robots [9].

Flying robots are used by military, security, civil and commercial applications in areas such as correction and relaying of real-time data of an occurrence. They enable effective responses in areas like disaster zones, farming, reconnaissance, environmental observation and monitoring, meteorological observation and research, and mineral exploitation etc. [10]–[12].

Key for swift and flexible mobility controllability and operation of flying robots is the wireless communications for which antennas are an essential element. A firm, compact, low profile aerodynamic enhancing antenna mounted on a robot facilitates reliable drone-controller communication.

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In most cases, this antenna should provide omnidirectional radiation pattern and vertical polarisation for efficient communication with the controller [13].

3D inkjet printing with nanoparticle silver ink is a rapidly advancing manufacturing method. It is a layer by layer fabrication process where a design can be printed directly from a digital model. It offers rapid prototyping and can reduce manufacturing process cycles in areas such as electronics, microwave and radio frequency (RF) [14].

Inkjet printing has been employed in the development of antennas on various substrate such as 3D printed polylactic acid (PLA) [15], [16] thermoplastic acrylonitrile butadiene styrene polycarbonate (ABS-PC) [17], polyethylene terephthalate (PET) [18], flexible thermoplastic polyurethane (NinjaFlex) [19], textile [20], Rogers RO 3203 [21] etc. Further developments on inkjet printing technology have enabled printing of antennas on paper-based substrates [22]–[27]. Examples include monopole antennas and designs suitable for RFID applications [22], ultra wideband antennas [23]–[25], and fractal geometries based on a triangular Sierpinski concept [26]. Miniaturized MIMO antennas have also been proposed by printing on a Kodak film paper which are then folded on a cylindrical shape [27].

This article investigates the integration of inkjet-printed antenna on a flying robot that is produced using traditional origami techniques. This type of flying robots are gaining popularity in the research and development community [28], [29]. A compact dual-band antenna consisting of a triangular shape with a horizontal slot on top of a semi-elliptical monopole is employed. Low-cost inkjet printing on photo paper substrate is used. It is the first time that a geometry has been developed to specifically fit within the folds of a traditional origami bird folded from an A4 paper sheet. Three positions are found to be suitable for the antenna: triangular neck, spine and tail. Consequently, two versions of the same antenna designs are produced. One fits on the robot’s spine while the other fits on the tail and/or the neck. The latter is further investigated in a diversity configuration.

The rest of the paper is organized as follows: Section ? describes the design and analyses the antenna located on the spine, section ? studies the antenna located on the tail, section ? describes diversity antenna system solution while section ? is the conclusion and discussion.

II. DESIGN AND ANALYSIS OF THE SPINE ANTENNA

A. ANTENNA DESIGN ANALYSIS AND GEOMETRY

A traditional flapping origami robot with potential electromechanical and antenna components locations is illustrated in Fig.1. Fig. 2(a) shows the fold lines along which the origami bird is folded from a 210 mm square (about A4 size) sheet. It also shows the location for a spine antenna. The bands targeted for the flying robot application are 2.4 GHz and 5.2 GHz WLAN/WiFi communication bands [30], [31]. The proposed planar monopole antenna (Fig. 2(b)) is based on [32], [33] and its geometry is modelled around [34]. It is a leaf shaped monopole with a semi-elliptical bottom and a

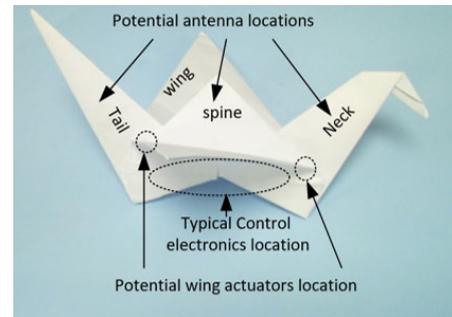


FIGURE 1. The origami robotic bird and potential antenna locations.

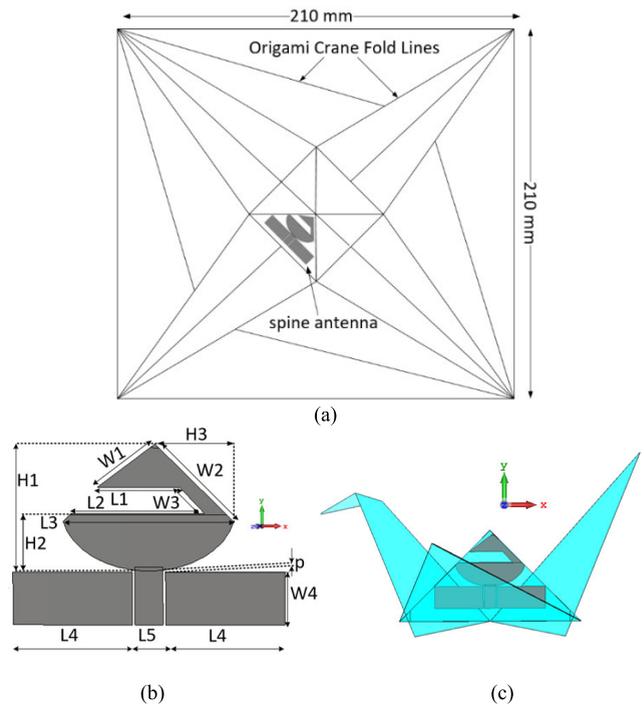


FIGURE 2. Antenna integrated onto the Spine of the origami crane: (a) illustration of the spine antenna in the unfolded robot layout, (b) the optimized antenna and (c) location on robot.

triangular top with a horizontal slot. Its dimensions are given in Table 1. The lower semi-elliptical section fit in the lower wider section of the triangular spine while the triangular upper part fits in its apex as shown in Fig. 2 (c). The antenna orientation is as that of the spine i.e. upright. A 50Ω CPW line feeds the antenna. Two rectangular ground plane are on either sides of the CPW feed line.

The lower frequency (f_L) of a planar elliptical disc monopole corresponding to $VSWR = 2$ is approximated by equating its area to the area of an equivalent cylindrical monopole of the same height L and equivalent radius r :

$$2\pi rL = \pi R_1R_2 \tag{1}$$

where R_1 and R_2 are the longer and shorter half lengths of ellipse’s axes respectively. Equation (1) thus gives:

$$r = (R_1R_2)/2L \tag{2}$$

A quarter wavelength monopole antenna has an input impedance equivalent to half of that of a half wavelength

TABLE 1. Antenna optimum dimensions in millimeters (mm).

Dimensions	L1	L2	L3	L4	L5	W1	W2
Value (mm)	15.4	25.1	32.2	22.5	5.3	13.6	19
Dimensions	W3	W4	H	R1	R2	p	
Value (mm)	2.2	6.9	24.24	11.75	16.8	0.4	

dipole antenna. The input impedance of an infinitesimally thin monopole antenna is thus $36.5 + j21.25\Omega$, an inductive impedance. The real impedance is obtained by using a slightly smaller length, L , of the monopole given by [35].

$$L = 0.24\lambda F \tag{3}$$

where λ is the free space wavelength and F is the length-to-radius parameter for the stub monopole given by

$$F = (L/r) / (1 + L/r) = L/L + r \tag{4}$$

From equations (3) and (4), the wavelength λ is obtained as:

$$\lambda = (L + r) / 0.24 \tag{5}$$

Thus the lower frequency f_L is:

$$f_L = c/\lambda = (30 \times 0.24)/(L + r) = 7.2/(L + r) \tag{6}$$

After accounting for the effect of probe length, p , which increase the antenna length and thus reducing the frequency, (6) can accordingly be modified to

$$f_L = 7.2/(L + r + p) \tag{7}$$

where f_L is in GHz and L , r and p are in cm. For the half lengths axes R_1 and R_2 , the ellipticity ratio, R_1/R_2 , chosen was 1.3 to restrict the bandwidth to the range of interest. The antenna was fed along the minor axis of the semi ellipse. For elliptical monopole fed along the minor axis, $L = 2R_2$ and $r = R_1/4$. For a f_L equal to 2.4 GHz, the radii R_1 and R_2 of the semi-ellipse after optimization were obtained.

A planar triangular monopole of height H (height from feed point to apex) and base length W was superimposed on the semi elliptical monopole. H is the height of the equivalent cylindrical monopole of radius r . H and r are calculated from (6), (8) and (10):

$$H = \sqrt{3}W/2 \tag{8}$$

$$r = W/4\pi \tag{9}$$

The actual height H is less than the calculated height due to dielectric substrate and fringing currents effect. It should be noted that the superimposed rounded triangular monopole base is the semi-elliptical disc.

The model was simulated on a 0.177 mm thick paper substrate of relative permittivity, ϵ_r , of 3 using CST Microwave StudioTM. Fig. 3 shows the response of the various component of the radiator. The semi elliptical radiator provides a resonant at upper band. The semi-elliptical radiator with superimposed triangular monopole exhibits wide-band characteristics. The lower frequency is higher than the targeted 2.4 GHz. This could be due to the rounded (semi-ellipse) base of the triangular monopole which reduces

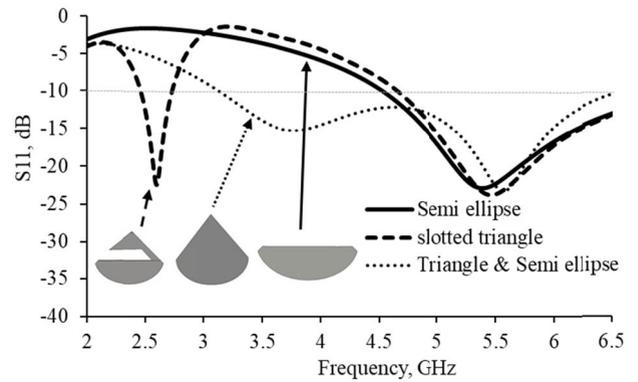


FIGURE 3. Radiating element configuration for respective resonance.

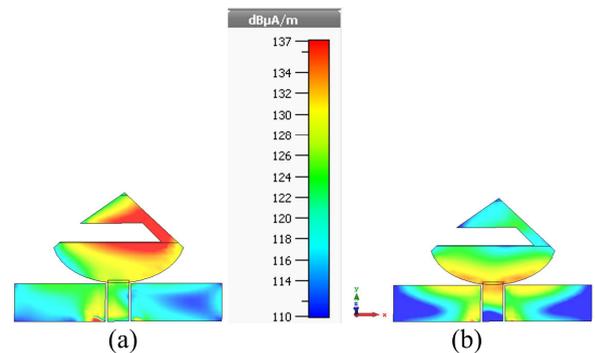


FIGURE 4. Surface current distribution for spine antenna (a) 2.4 GHz and (b) 5.2 GHz.

the size of radiator thus raising f_L . By inserting and optimizing the dimension of a horizontal slot across the triangle, the lower resonance point was shifted to 2.4 GHz while maintaining the upper band as well as rejecting frequencies between the two bands of interest. The final antenna has two distinct resonant modes corresponding to the triangular radiating section and the semi ellipse. The gap ‘ p ’ between the ground plane and radiating acts as a matching network and improves impedance bandwidth. The optimum impedance bandwidth is achieved when the capacitance due to the gap ‘ p ’ between the radiating element and ground plane edges balances with the antenna inductance.

The size of the ground plane is also critical in the design of compact antennas [36], [37]. The surface current distribution on the antenna is shown in Fig. 4. As expected, at 2.4 GHz,

Fig. 4 (a), most of the currents is concentrated in the triangular section. At 5.2 GHz, Fig. 4 (b), most of the currents are in the lower section of the semi-ellipse. As with all compact antennas on small ground planes, some currents are also present on the antenna’s ground elements. These currents are strongest at the upper edges of the rectangular ground planes at 5.2 GHz than at 2.4 GHz. Taking this into consideration, it can be inferred that the surface current distribution could change with the size and the shape of the ground plane and/or with introduction of cable and/or RF connector to the antenna. This is likely to introduce differences in the measurements in relation to simulations.

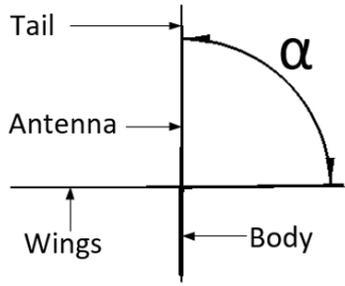


FIGURE 5. Wing angle α relative to the wings horizontal position.

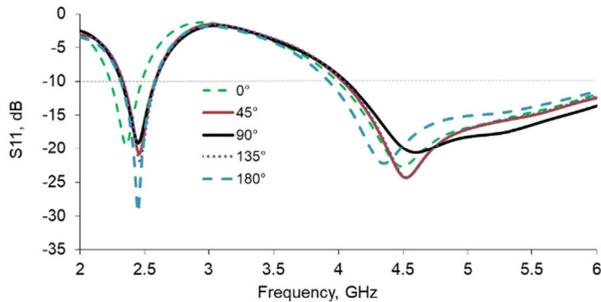


FIGURE 6. Effect of change of angle α on the reflection coefficient.

B. INVESTIGATION OF EFFECT WINGS MOVEMENT

The effect on the antenna performance by the wings' flapping during flight was investigated. Fig. 5 depicts the flap angle α of the wings in relation to vertical core of the bird structure. Fig. 6 shows the simulation reflection coefficients (S_{11}) for various values of α : 0° , 45° , 90° , 135° and 180° . The horizontal position of the wings was defined as the 90° position. The wings extreme upward flap was designated as 0° and the extreme downward as 180° . In the horizontal position, -10 dB impedance bandwidth of the antenna is from 2.3 GHz to about 2.6 GHz at the lower band and from 4 GHz to 6 GHz at the higher band. There is no significant change in S_{11} from 1° to 180° . Only angles of less than 1° produced an S_{11} higher than -10 dB at the target 2.4 GHz to 2.5 GHz band. In the worst scenario, at 0° , the S_{11} was less than -8 dB across the 2.4 GHz band.

C. SPINE ANTENNA FABRICATION AND MEASUREMENTS

The CST model was exported to Gerber (single layer) and then converted to a PDF file using ViewMate. The PDF was then printed using silver nanoparticles ink that is based on chemical sintering. Chemical sintering technology was used to avoid the prolonged heat sintering and the damage it can cause when the substrate used is a paper based material [38]. In chemical based sintering, a polymer latex and halide emulsion solvent dissolves silver nanoparticles of less than $0.1 \mu\text{m}$. Conductivity appears moments after the solution has dried. This makes the ink based on chemical sintering ideal for inkjet printing of the antennas. A 1200×6000 dpi resolution and piezo with 210×3 colour print head home desktop Brother MFC-J5910DW printer was employed. AgIC-AN01 Silver Nano Ink was loaded in the 3 colour

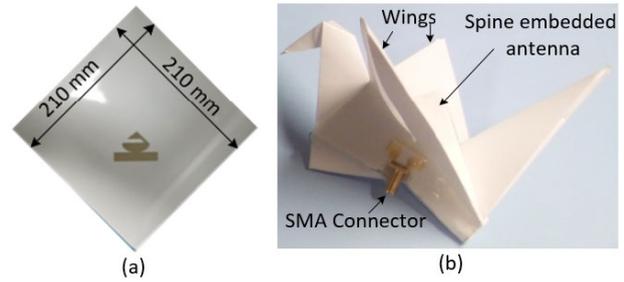


FIGURE 7. (a) Photo paper printed tail antenna folded into a (b) folded into a robotic bird.

cartridges to produce a thick print layer that can achieve sufficient conductivity. The silver ink provides a resistivity of $0.2 \Omega/\text{sq}$ when printed on an AgIC-CP01A4 photopaper [39]. Further analytical tests on a variety of printed tracks were carried out using the equation for the resistivity, ρ :

$$\rho = R \frac{A}{l} \quad (10)$$

where R is the measured resistance, A is the cross-sectional area and l is the length of the track. The values of resistivity obtained were between 2×10^{-7} and 3×10^{-7} which is about the same value to the one provided by the manufacturers for a layer thickness of about $1 \mu\text{m}$.

The printed antenna is shown in Fig. 7(a). The printout was folded into a robotic bird. The antenna was concealed inside the structure to protect the printed metallic layers from environmental damage as shown in Fig. 7(b) Thermal and mechanical stability of the printed layers were provided by AgIc. Heat resistance can be allowed for up to 30 minutes at 100°C . In cross cut tests (ISO 2409), the mechanical stability is between 0 to 1 (0 is highest and 5 is lowest).

Surface profiles of the antenna's silver ink were obtained using white light interferometry (profilometer). The images at $50\times$ magnification are shown in Fig. 8(a). An average surface roughness of approximately $S_a 200\text{nm}$ was obtained. The image shows that the 3D print is not uniform as the substrate can be seen through the silver ink. The droplets are visible and the measured roughness is for both paper substrate and silver droplets. Fig. 8(b) is an optical image of top view of the printed antenna of $1 \mu\text{m}$ silver ink height taken with $\times 10$ magnification which shows uneven surface. Black regions are seen within the sample which could be deeper unevenness of ink surface. Fig. 8(c) shows the narrow gap between CPW and the ground plane taken with $\times 20$ magnification for the $1 \mu\text{m}$ silver ink height. Some isolated silver ink particles can be seen inside the gap but their isolation prevents short circuit across the two parts. The presence of ink particles in the gap does not have any significant effect on the performance of the antennas as the foregoing tests shows. This could be because the particle sizes are much smaller compared to the wavelength of the frequencies involved.

To test the antenna, a 3.5 mm SMA connector was attached to it using Araldite Rapid Epoxy Adhesive. The antenna was concealed inside the structure to protect the printed metallic layers from environmental damage. A Rohde & Schwarz

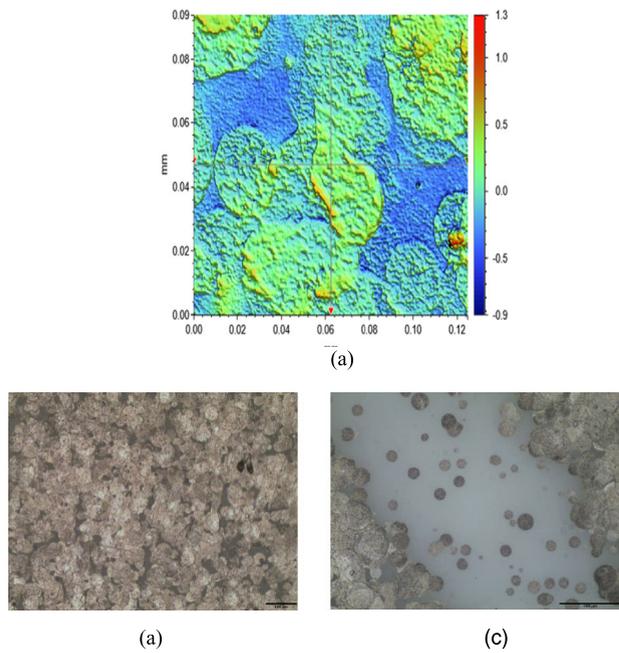


FIGURE 8. (a) Silver paint optical interferometry image (b) Silver ink top view optical microscopic image (c) image of the gap between CPW and the ground plane.

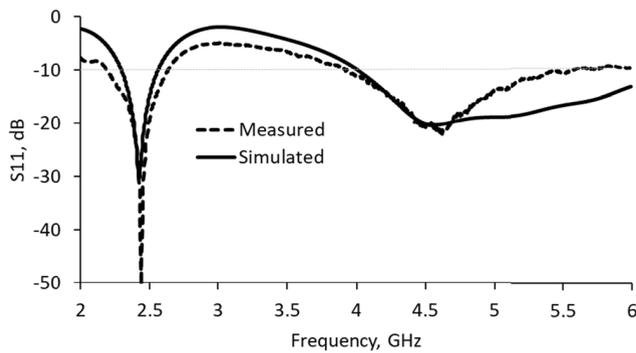


FIGURE 9. Measured and simulated S_{11} compared.

ZVL vector network analyser was used for S_{11} measurements. Fig. 9 shows the simulated and measured S_{11} when the wings are horizontal. The measured lower band has -10 dB impedance bandwidth from 2.2 GHz to 2.7 GHz while the upper band has a bandwidth from 3.9 GHz to 5.5 GHz thus covering both target bands. The slight discrepancy between the simulated and the measured S_{11} could be due to fabrication, folding and measurements errors. These includes non-uniformly deposited silver conductive ink and resistive losses of the printed tracks, the bending of the substrate, as well as the SMA connector.

Fig. 10 shows the simulated and measured radiation patterns at (a) 2.4 GHz and (b) 5.2 GHz for the robot's horizontal wing position i.e. α is equal to 90° . The simulated results show that as expected for this type of antennas, the planes xy and yz has nulls in the y axis while plane xz displays an omnidirectional pattern. Tests showed no significant effect on the radiation pattern when the position of the wings is varied

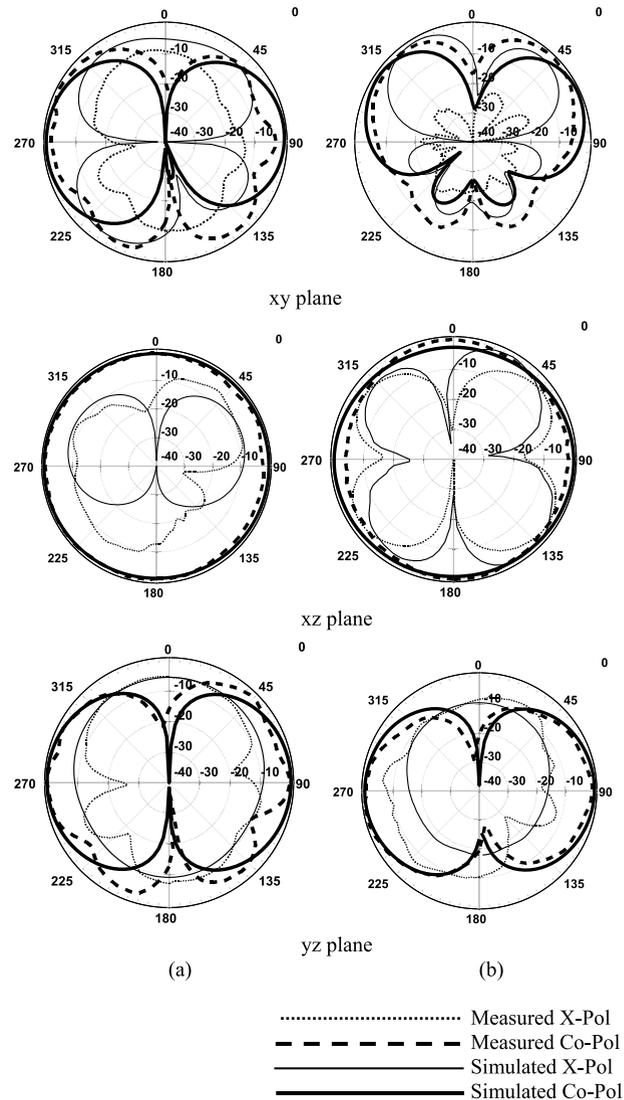


FIGURE 10. Simulated and measured radiation pattern for planes xy, xz and yz at (a) 2.4 GHz and (b) 5.2 GHz.

from 0° to 180° relative to the robot's core. The measured antenna radiation patterns are consistent the simulations. As with planar monopoles [40], it exhibits high cross polarization. The high cross polarization component as a result of excitation order modes, radiation due to J_x current at the top edges of the ground plane near the radiating element. Discontinuity at substrate and metallic radiator results in surface waves adding to cross polarization [41]. Fig. 11 shows the gain vs frequency response for the selected frequency bands. The measured antenna gains were 1.4 dBi and 2.7 dBi at 2.4 GHz and 5.2 GHz respectively, about 0.2 dB and 0.5dB lower than the simulated one. The differences between the simulated and measured gain could be due to fabrication and folding errors, cables and connectors.

III. A SINGLE CPW-FED TAIL ANTENNA

A. TAIL ANTENNA DESIGN

An alternative antenna location is the tail of the origami crane. Fig. 12(a) illustrates the location of a tail antenna

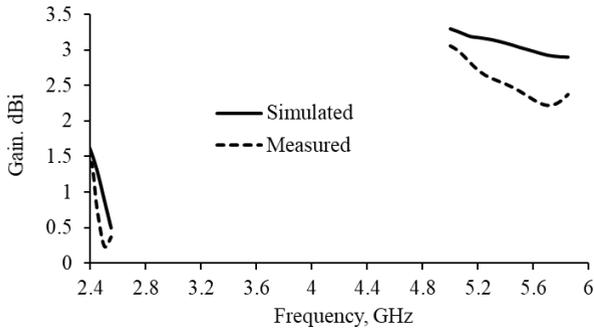


FIGURE 11. Spine antenna gain-frequency response at 2.4 and 5.2 GHz.

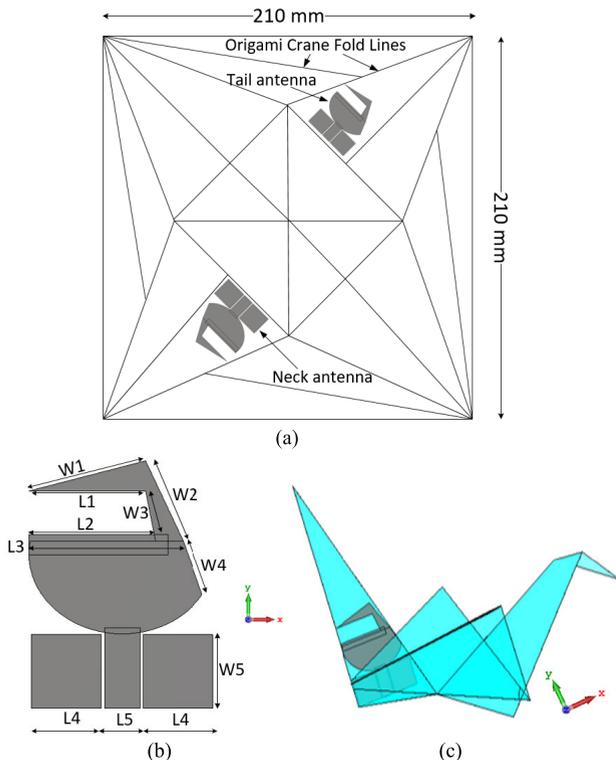


FIGURE 12. Antenna integrated onto the tail of the origami crane: (a) illustrative tail and neck antennas location in the unfolded layout, (b) tail antenna and (c) location on the robot.

as well as the potential symmetrical location for a neck antenna, on 210 by 210 mm unfolded photo paper substrate. Fig. 12 (b) show the antenna’s structure and dimensions while Fig. 12(c) shows its location on the robot’s tail and rotated to fit on the tail’s orientation. Like the previous antenna, the antenna is concealed inside structure to protect the printed metallic layers from environmental damage. The antenna is similar in shape and construction to that described in section IIA with slight dimension adjustments to fit in the narrower tail area and achieve the bandwidths of interest. Table 2 show its final dimensions. The same dielectric material and substrate thickness was used.

The simulated S_{11} results, Fig. 13, indicates a narrower -10 dB bandwidth at the 2.4 GHz band but a wider -10 dB bandwidth at the 5.2 GHz bands for the angle α of wing

TABLE 2. Final dimensions of the optimized tail antenna (MM).

L1	L2	L3	L4	L5	W1	W2	W3	W4	W5
17.5	19	23	10.5	5.8	18	13.28	7.65	8.55	11

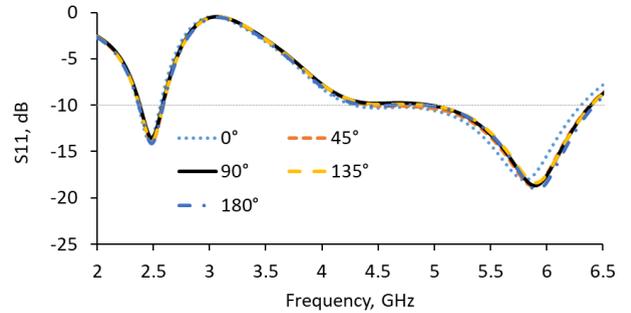


FIGURE 13. Tail antenna simulated S_{11} for angle α .

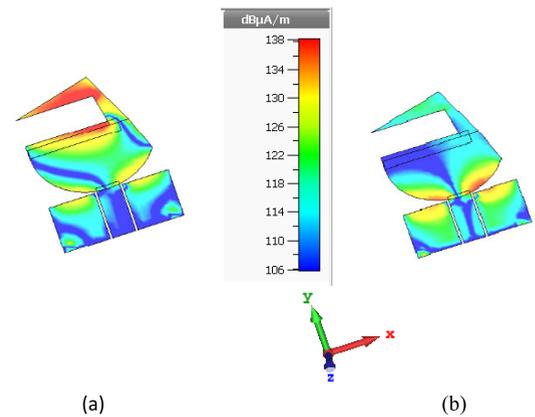


FIGURE 14. Surface current distribution for tail antenna (a) 2.4 GHz and 5.2 GHz.

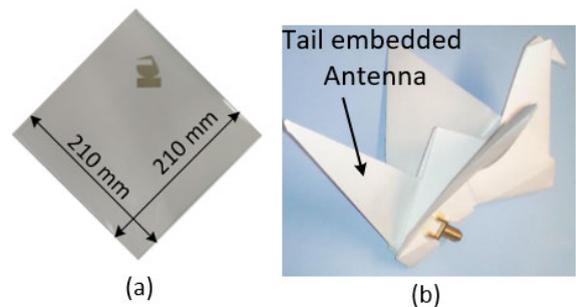


FIGURE 15. (a) Tail antenna printed on a photo paper and (b) folded into a robotic bird.

the flapping. The antenna covers the desired frequency bands for the range of angles of flap. They also show a near negligible effect on S_{11} by the flapping of the wings. This could be due to the antenna on the tail being removed from the wings bearing section of the origami bird structure. This makes the antenna less obstructed by the flapping of the wings compared to the antenna on the spine (Fig. 7b).

Fig. 14(a) and Fig. 14(b) depicts the surface current distribution at 2.4 GHz and 5.2 GHz respectively. The figure

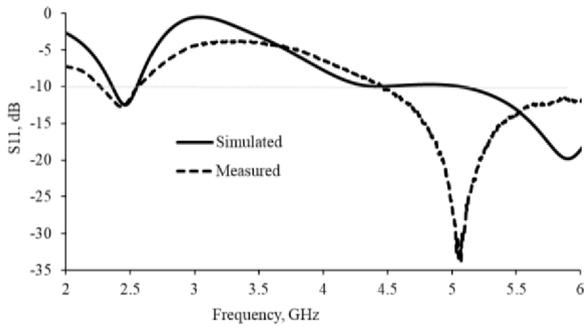


FIGURE 16. Measured vs simulated tail antenna S11.

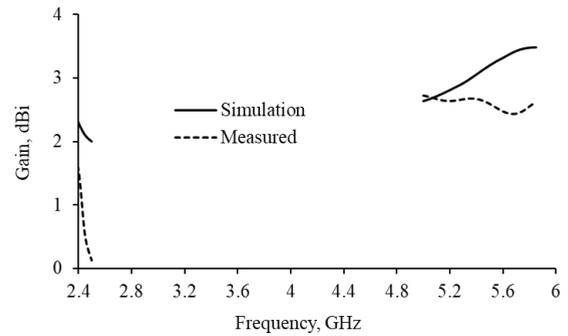


FIGURE 18. Tail antenna gain-frequency response at 2.4 and 5.2 GHz.

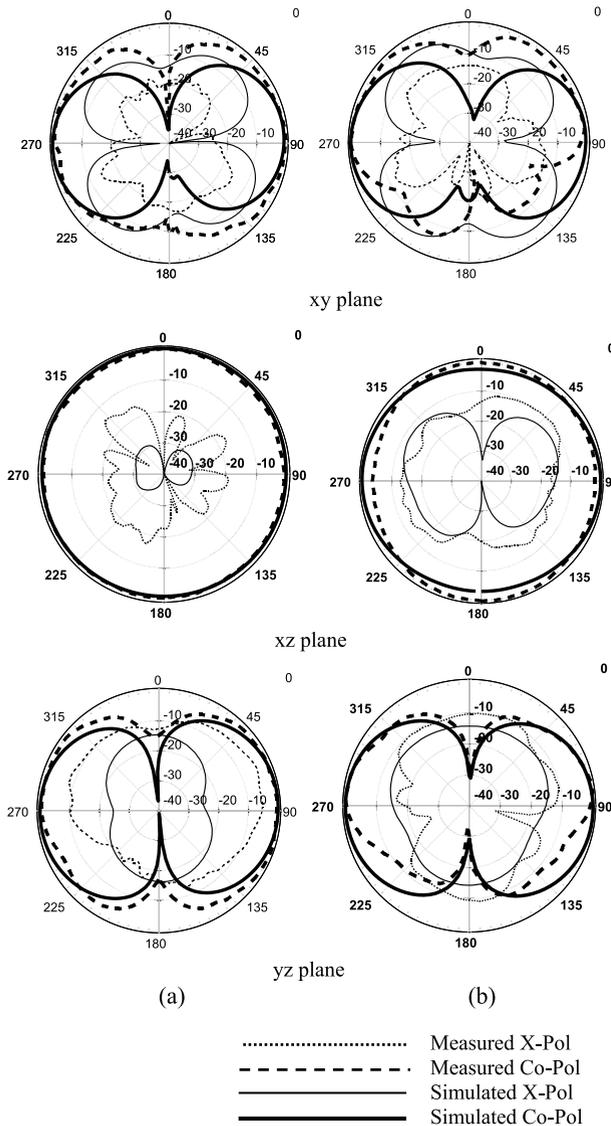


FIGURE 17. Simulated and measured radiation patterns for xy, xz, and yz planes at (a) 2.4 GHz and (b) 5.2 GHz.

indicates a high level of surface current at the triangular and rounded sections of the antenna at 2.4 GHz and 5.2 GHz resonance points respectively. A high surface current level is also observed on the ground plane at the two bands due to its small size which makes it a sensitive part of the radiating structure [37].

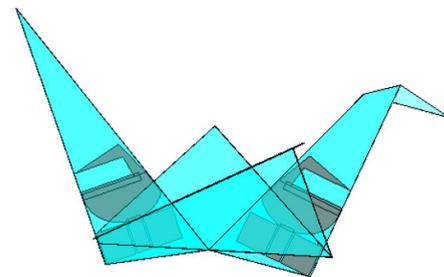


FIGURE 19. Simulated neck diversity antenna.

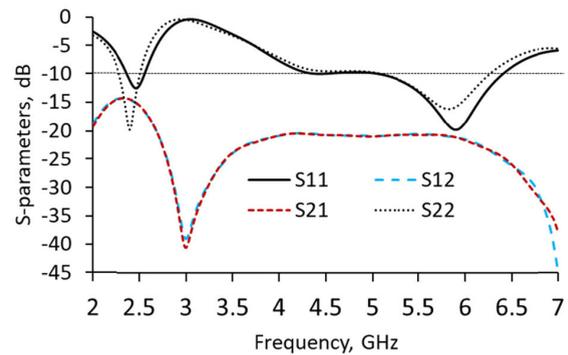


FIGURE 20. Simulated diversity antennas S-parameters.

B. FABRICATION AND MEASUREMENTS

The fabrication procedure used in section IIC was followed for the tail antenna. Fig. 15(a) shows the printed tail antenna on a photo paper and Fig. 15(b), the origami crane after the paper is folded up. S_{11} of less than -10 dB at both 2.4 GHz and 5.2 GHz bands compares well to that of the simulation as shown in Fig. 16 for flap angle α of 90° . Fig. 17 shows simulated and measured antenna radiation pattern at (a) 2.4 GHz and (b) 5.2 GHz bands. Both planes xy and yz have nulls in the y-axis while plane xz indicates omnidirectional radiation. There are differences between the measured and the simulated radiation pattern. This could be due to the small ground plane and the introduction of RF connector/cable to the antenna which affects the current distribution in the ground plane. This changes the impedance and radiation performance. This results in the measured results being slightly different from the simulated results and potentially can make the design validation difficult.

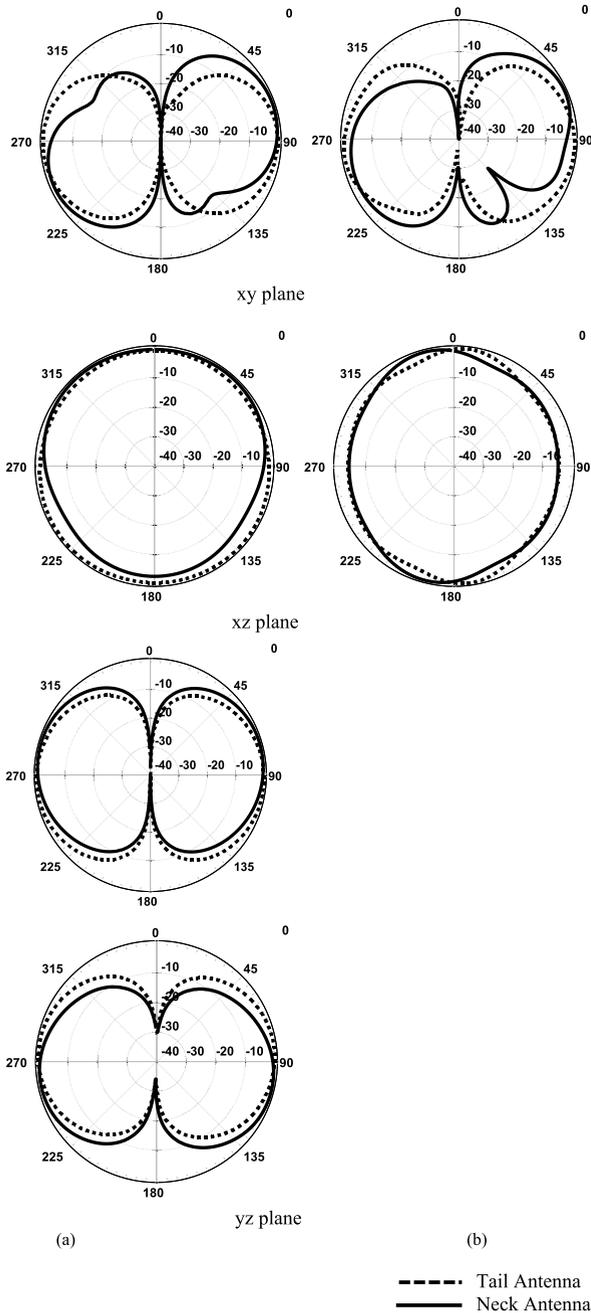


FIGURE 21. Simulated diversity antenna radiation pattern for planes xy, xz, and yz at (a) 2.4 GHz and (b) 5.2 GHz.

Fig. 18 shows the measured and simulated gain versus frequency response at the two frequency bands of interest (2.4-2.5 GHz and 5.0-5.9 GHz). The measured gains are in general lower than simulation ones. The measured gains were about 1.5 dBi at 2.4 GHz and about 2.5 dBi at 5.2 GHz.

IV. DIVERSITY ANTENNA SYSTEM SOLUTION

A. DIVERSITY ANTENNA SYSTEM DESIGN

Antenna diversity enables improvement of radio communication and enhances the probability of a signal from a transmitter reaching a receiver in a dynamic environment [42] by reducing signal fading, increasing the coverage of the communication system etc.

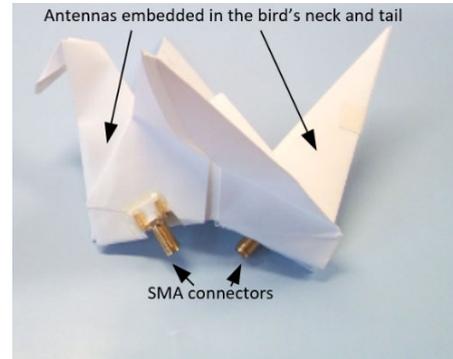


FIGURE 22. Fabricated diversity antenna.

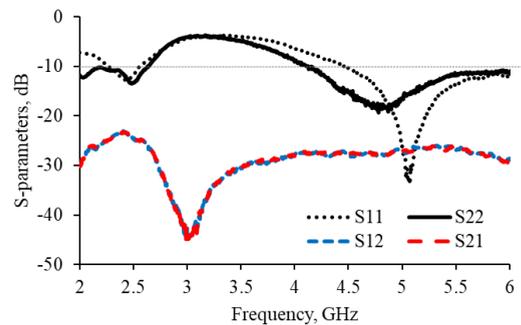


FIGURE 23. Measured diversity antenna S-parameters.

A diversity antenna was created on the neck of the crane, as illustrated in Fig. 19 and also rotated to fit the neck orientation. Each antenna requires an independent RF circuitry and electronics connection and ability to communicate with the control station. The S-parameters i.e. S_{11} , S_{12} , S_{21} and S_{22} of the simulated model were obtained and are shown in Fig. 20. S_{11} curve is slightly different from S_{22} curve. This is due to the robot’s wings extending over the front antenna and acting as an extra layer of substrate. S_{11} of -10 dB impedance bandwidths from 2.36 GHz to 2.55 GHz at the lower band and 5.07 GHz to 6 GHz at the higher band respectively were realized. S_{22} of -10 dB impedance bandwidths from 2.27 GHz to 2.50 GHz and 5.11 GHz to 6 GHz at lower and upper bands respectively were realized. S_{12} and S_{21} of less than -10 dB at the resonance frequencies indicates a good antenna isolation between the two antennas. Simulated diversity antennas co-polarization radiation patterns are shown in Fig. 21 (a) at 2.4 GHz and (b) at 5.2 GHz bands for planes xy, xz and yz for the tail and neck antenna. The radiation pattern indicates nulls about the y-axis for xy and yz planes and an omnidirectional radiation pattern for the xz plane for both the tail and neck antennas at both bands. There is improvement in coverage in all planes compared to just one antenna on the tail. The radiation patterns of the two antennas are generally in the same direction that could be due to the two antennas being similarly orientated.

B. FABRICATION AND MEASUREMENT

The diversity antennas were fabricated, Fig. 22, as per the procedure described in section 11C. A VNA was used to

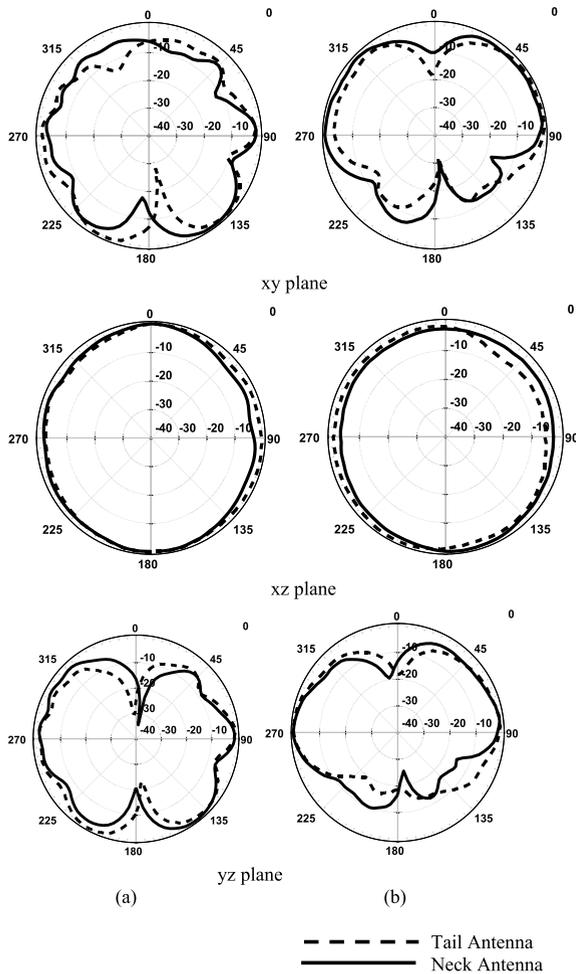


FIGURE 24. Measured diversity antenna radiation patterns for planes *xy*, *xz* and *yz* at (a) 2.4 GHz and (b) 5.2 GHz.

measure the S-parameters whose plots are shown in Fig. 23. An $S_{11} - 10\text{dB}$ impedance bandwidth from 2.3 GHz to 2.55 GHz at the lower band and 4.5 GHz to 6 GHz at the upper band respectively was achieved for a flap angle α of 90° . An $S_{22} - 10\text{ dB}$ bandwidth from 2.2 GHz to 2.65 GHz at the lower band and 4.3 GHz to 6 GHz the upper band respectively was also realized. S_{12} and S_{21} of less than -23 dB at both 2.4 GHz and 5.2 GHz bands indicates good isolation between the two antennas.

The orientation of the axis for the measurement of the radiation pattern of the neck is symmetrically to that for the tail. Fig. 24 depicts the measured radiation patterns of planes *xy*, *xz* and *yz* respectively at (a) 2.4 GHz and (b) 5.2 GHz for the two antennas. It indicates nulls in the *xy* and *yz* planes and omnidirection in the *xz* plane for two frequency bands which is commensurate with simulation results. As expected, the radiation patterns for the two antennas are similar. Improvement in coverage is expected when connected to a diversity antenna system.

Table 4 compares previous dual bands WLAN inkjet printed antennas with the one proposed in this work. It can be seen that with comparable gain and bandwidth, the proposed antenna is relatively small in size and is the only one

TABLE 3. Comparison between the proposed antenna and previous WLAN Inkjet printed antennas.

Reference	Freq. (GHz)	Bandwidth (GHz)	Gain (dB)	Substrate	Size (mm ³)
[19]	2.4	1.12	-7.2	NinjaFlex	65×54×1.2
[43]	2.45	0.77	1.81	PET	45×40×0.14
	5.8	2.91	3.92		
[45]	2.4	0.9	3.74	Paper	54×57×0.18
	5.8	2.9	4.96		
This work	2.4	0.45	1.40	Paper	51×34×0.18
	5.2	1.60	2.78		

specifically designed to fit the space available in the origami flapping crane.

V. DISCUSSION AND CONCLUSION

The integration of inkjet printed planar monopole antennas on an origami flapping robot has been demonstrated. A wideband monopole antenna consisting of a semi-elliptical shape with a triangular part and a horizontal slot has been developed and tested. The dimensions of the triangular section determine resonance at 2.4 GHz while the dimensions of the semi-elliptical section determine resonance at the 5.2 GHz band, the unlicensed frequency bands for drones' control.

The antenna fits on the available space on the traditional origami structure and is able to operate at the required bands. Two optimal solutions were achieved: one on the spine and the other on tail and/or neck.

A diversity system involving the tail and neck antennas was also realized. This increases coverage in a communication system. All the antennas exhibited nearly omnidirectional radiation pattern in the XZ planes at both frequency bands making them suitable for the purpose. The monopole antennas have been fabricated on standard photo paper substrate. A chemical sintering-based silver nanoparticle conductive ink cartridge was used to print the antennas using an inexpensive and ordinary home inkjet printer and photo paper. This made fabrication of the antenna cheap and fast. The successful outcome promises the potential of integration of antennas with flexible electronic systems using inkjet printing technology.

This holds out prospects of appropriation of instant printing technology for fast integration of antenna and flexible electronic systems on paper substrate for future wireless controlled aerial robots in line with [45]. This promises potential realization of other electronics components on a paper substrate as well as potential realization of fully integrated expendable robot.

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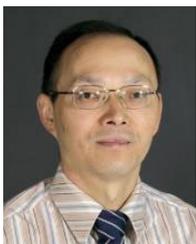
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