

VEGA 1/0367/15 Research and development of a new system for autonomous robot trajectory control

The project has been focused on the implementation of hybrid sensors – Inertial Navigation System (INS), into robot's control. A system with such a control can acquire a precise position of robot's effector in space. The application can be used for calibration of a robotic workplace. The calibration is necessary in order to adapt a simulated model of a production device to real geometric conditions. A simulation model of a production device and robot programming set represent an accurate representation of reality. However, an absolute correspondence with the reality cannot be expected. Deviations of reality from simulation occur because of several reasons. The implemented IND will be used for calibration without the use of calibration equipment, thereby enabling a significant simplification of calibration in practice.

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Some of publications:

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