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A new Software Driven external Sensor System for Industrial Robots

Bernd Bertschinger^a, Kathrin Hoffmann^b, Jan Baumgärtner^c, Gajanan Kanagalingam^b

^a*Institute of Applied Optics, University of Stuttgart - ITO, Pfaffenwaldring 9, 70569 Stuttgart, Germany*

^b*Institute for System Dynamics, University of Stuttgart - ISYS, Waldburgstr. 17/19, 70563 Stuttgart, Germany*

^c*Institute of Production Science, Karlsruhe Institute of Technology - WBK, Kaiserstraße 12, 76131 Karlsruhe, Germany*

* Bernd Bertschinger Tel.: +49-711-685-69892 ; fax: +49-711-685-66072. E-mail address: bernd.bertschinger@ito.uni-stuttgart.de

Abstract

For decades, laser tracker and working station have been the state of the art to measure externally the position disturbances in robotic systems. High system costs limit their usage for control systems in common production machines. We present details for an alternative software-driven approach. Hereby, we combine a new self-referencing, high-precision photogrammetry sensor system with a software system for camera placement layout and trajectory optimization. Furthermore, we outline the integration in a closed loop control system and corresponding strategies.

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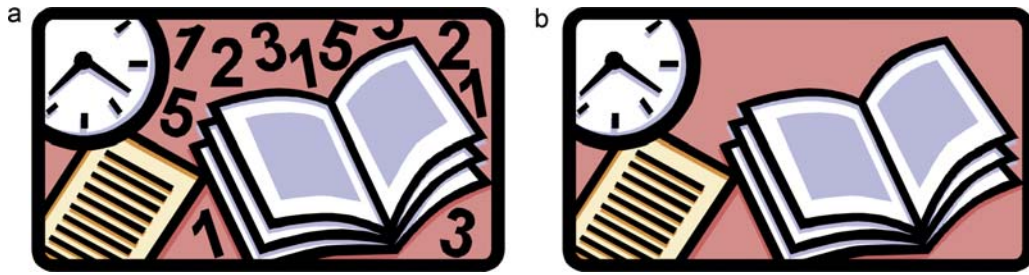


Fig. 1. (a) first picture; (b) second picture.

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$$\rho = \frac{\vec{E}}{J_c(T = \text{const.}) \cdot \left(P \cdot \left(\frac{\vec{E}}{E_c} \right)^m + (1 - P) \right)} \quad (1)$$

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References

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