**DITTO – THE ADVANCED LEAD THROUGH ROBOT**

**ABSTRACT:**

Recently robots are widely used in a various field particularly in the industry. Despite this fact robot still requires an undeniable amount of knowledge from the operators or workers who deal with them. As a result, robots cannot be easily programmed if the operator or the worker is not experienced in robotics field. One of the programming methods that has been introduced to make programming task user friendly is lead-through robot programming. However, the existing lead-through programming methods still requires an amount of knowledge that is not available for most of the operators and workers. The main objective of this project is to design a lead through method for point to point robot programming using angular and dimensional scaling of an real-time robot to a scaled down model, which can record, save and playback the robot motion while considering the accuracy and precision of the robot. This root the workers to not strain to program the robot by lead through the nose of huge real-time robot but through the scale downed duplicate. This ensures the method of programing much easier to use since, users need not to strive on robots. On the actual scenario of programing, the real-time robot offers resistance to motion which causes the operator to strain to move it to required positions. This issue can be overcome through this scaling method with greater reduction in latency of relocating the nose trajectory.

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