AI- Project

Collaborative HRI in industrial setting

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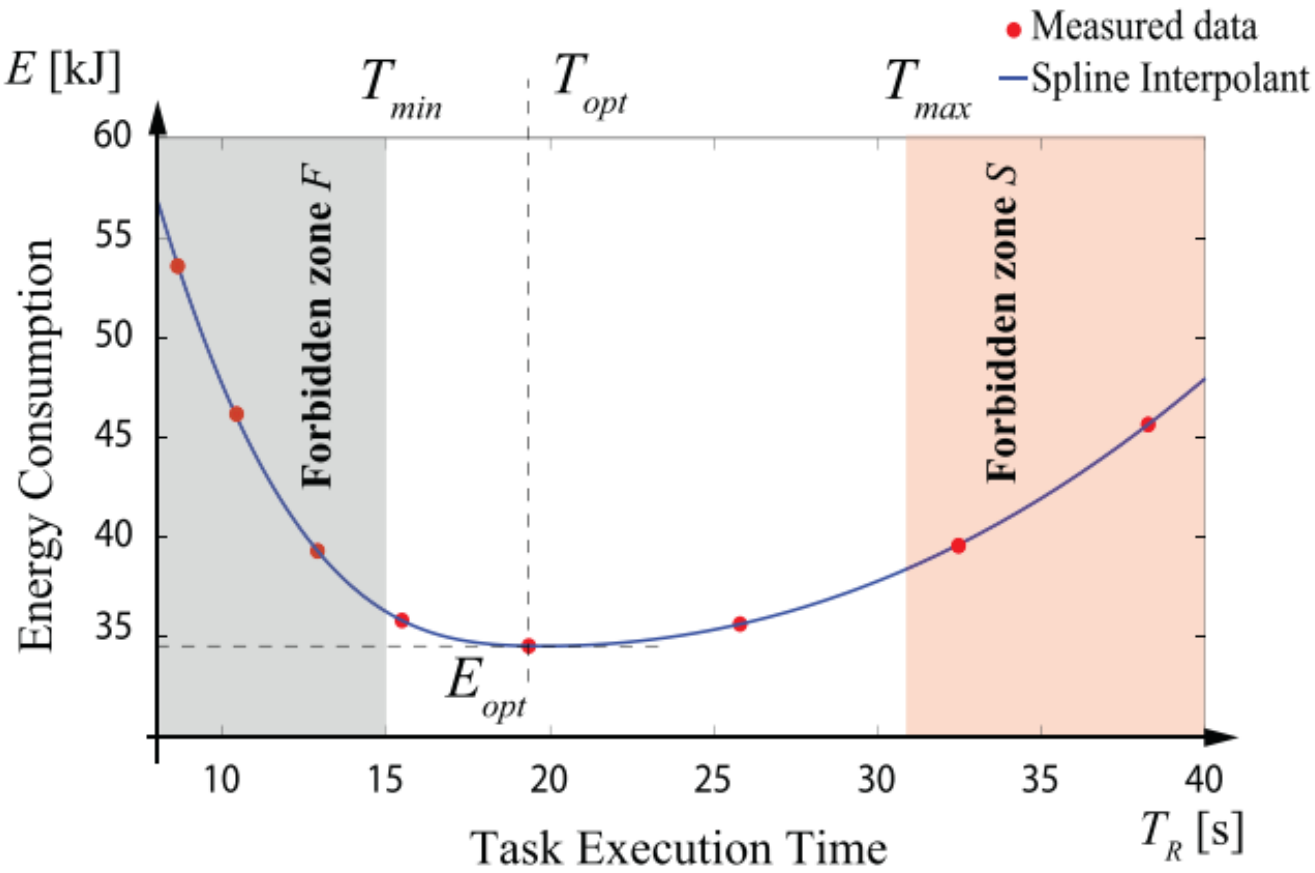
Planner

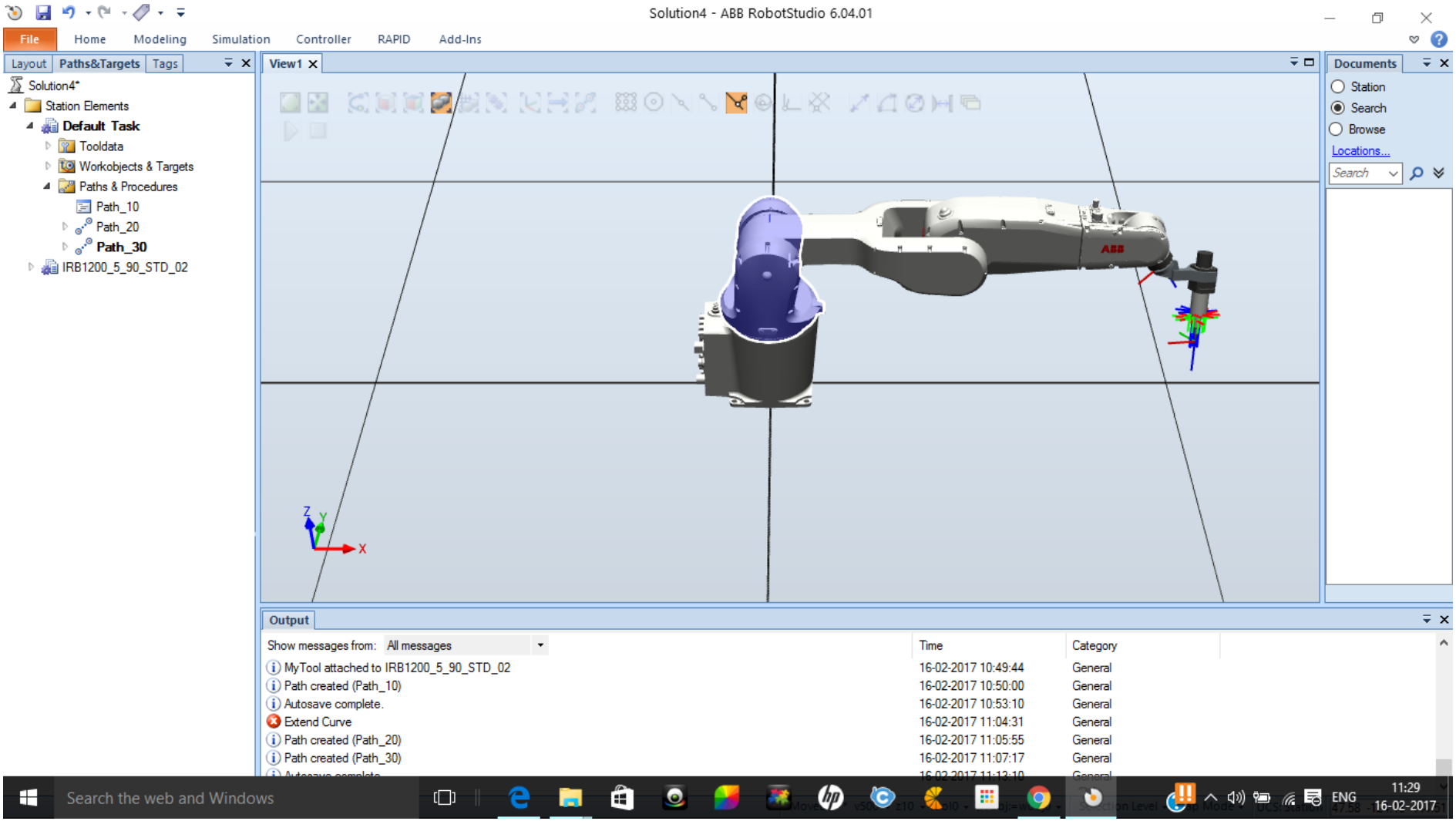


(b) Energy Consumption as a function of TET, T_O.

Fig. 1. Energy consumption in pick-and-place operations.

[1]

Trajectory


Solution4 - ABB RobotStudio 6.04.01
File
Home
Modeling
Simulation
Controller
RAPID
Add-Ins
Layout
Paths&Targets
Tags
Solution4*
Station Elements
Default Task
Tooldata
Workobjects & Targets
Paths & Procedures
Path_10
Path_20
Path_30
IRB1200_5_90_STD_02
View1
Documents
Station
Search
Browse
Locations...
Search
Output
Show messages from: All messages
Time
Category
MyTool attached to IRB1200_5_90_STD_02 16-02-2017 10:49:44 General
Path created (Path_10) 16-02-2017 10:50:00 General
Autosave complete. 16-02-2017 10:53:10 General
Extend Curve 16-02-2017 11:04:31 General
Path created (Path_20) 16-02-2017 11:05:55 General
Path created (Path_30) 16-02-2017 11:07:17 General
Search the web and Windows
ENG
11:29
16-02-2017

References

Koen Paes, Wim Dewulf, Karel Vander Elst, Karel Kellens, and Peter Slaets.
Energy efficient trajectories for an industrial abb robot.
Procedia CIRP, 15:105–110, 2014.