Workspace Analysis of a Dual-arm Mobile Robot System for Coordinated Operation

Yue Meng, Ziqi Zhao, Weinan Chen, Xiao Xiao, and Max Q.-H. Meng

Department of Electronic and Electrical Engineering, Southern University of Science and Technology, Shenzhen, China

- The mechanical and software structure of dual-arm mobile robotic system is introduced;

- D-H method is used to establish forward kinematics of the robotic arm;

- The workspace is analyzed by Monte Carlo method. The shape and boundary of the workspace is provided;

- Cooperative operation with the dual-arm is demonstrated.