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See application file for complete search history.

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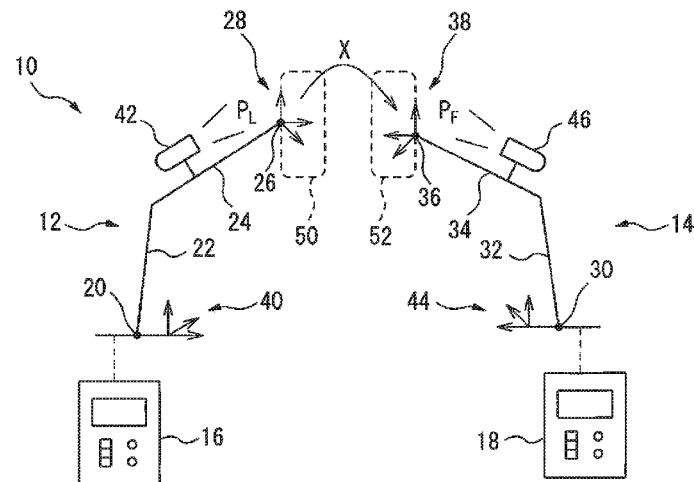
Primary Examiner — Jaime Figueroa

(74) Attorney, Agent, or Firm — Hauptman Ham, LLP

(57)

ABSTRACT

A robot system, a robot controller and a robot control method, by which a coordinated control of a plurality of robots can be taught while appropriately considering a positional deviation of each robot into consideration. A gripping misalignment of a first workpiece in a leading robot is detected, and then a first amount of correction for correcting the misalignment is calculated. Further, a gripping misalignment of a second workpiece in a following robot is detected, and then a second amount of correction for correcting the misalignment is calculated. In the coordinated control, a taught position/orientation of the leading robot is corrected based on the first amount of correction, and a taught position/orientation of the following robot is corrected based on both the first mount of correction and the second amount of correction.

3 Claims, 3 Drawing Sheets

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