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Titolo	Error Compensation for Industrial Robots // by Wenhe Liao, Bo Li, Wei Tian, Pengcheng Li
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Collana	Intelligent Technologies and Robotics Series
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Soggetti	Automatic control Robotics Automation Physics Industrial engineering Production engineering Measurement Measuring instruments Control, Robotics, Automation Robotic Engineering Applied and Technical Physics Industrial and Production Engineering Measurement Science and Instrumentation
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
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Nota di bibliografia	Includes bibliographical references.
Nota di contenuto	Part 1 Theories -- Chapter 1 Introduction -- Chapter 2 Kinematic modeling -- Chapter 3 Positioning error compensation using kinematic calibration -- Chapter 4 Error-similarity-based positioning error compensation -- Chapter 5 Joint space closed-loop feedback -- Chapter 6 Cartesian space closed-loop feedback -- Part 2 Chapter 7 Applications in robotic drilling -- Chapter 8 Applications in robotic milling.
Sommario/riassunto	This book highlights the basic theories and key technologies of error compensation for industrial robots. The chapters are arranged in the order of actual applications: establishing the robot kinematic models,

conducting error analysis, conducting kinematic and non-kinematic calibrations, and planning optimal sampling points. To help readers effectively apply the technologies, the book elaborates the experiments and applications in robotic drilling and milling, which further verifies the effectiveness of the technologies. This book presents the authors' research achievements in the past decade in improving robot accuracy. It is straightforwardly applicable for technical personnel in the aviation field, and provides valuable reference for researchers and engineers in various robotic applications.

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