

Title (en)
METHOD FOR ADJUSTING A ROBOT ARM

Title (de)
VERFAHREN ZUM JUSTIEREN EINES ROBOTERARMS

Title (fr)
PROCÉDÉ DE RÉGLAGE D'UN BRAS ROBOT

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Application
EP 21712111 A 20210311

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Abstract (en)
[origin: WO2021190947A1] In a method according to the invention for adjusting a robot arm (1) which has at least one axis (10) with a drive structural member (11), an output structural member (12) mounted thereon, and a drive (M, G) with a motor (M) for moving the output structural member relative to the drive structural member, the output structural member, in particular when at least one further such axis (20) of the robot arm is at a standstill, is moved by the drive relative to the drive structural member, in particular at a maximum speed, which is reduced in comparison to automatic operation, in a search direction (S20) corresponding to a predefined movement direction in order to approach, in particular to overrun, a predefined adjustment position. This search direction is reversed (S70) and the output structural member is moved (S20) counter to the predefined movement direction in order to approach, in particular to overrun, the predefined adjustment position if, during the movement in the predefined movement direction, a collision of the output structural member with an end stop (13) on the drive structural member is detected and/or if, during the movement in the predefined movement direction, a collision of the drive structural member with an end stop on the output structural member is detected and/or if, during the movement in the predefined movement direction, a collision of the robot arm with itself or its environment (3) is detected.

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