



Hybride Kraft- und Positionsregelung (German Edition)

Thomas Morper

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Studienarbeit aus dem Jahr 2004 im Fachbereich Informatik - Sonstiges, Universität Karlsruhe (TH) (Institut für Prozessrechenstechnik, Automation und Robotik), Veranstaltung: Seminar Robotik, Sprache: Deutsch, Abstract: In dieser Seminararbeit geht es um die Einführung in die hybride Kraft- und Positionsregelung, einer Robotersteuerung bei der sowohl die Position des Roboterarms bzw. des Effektors als auch die ausgeübten Kräfte eine Rolle spielen (anstatt wie sonst üblich nur einer der beiden Faktoren).

Zuerst gibt es eine generelle Einführung in den Aufbau einer Steuerung eines Roboters und welche verschiedenen Techniken dafür in der Praxis eine Bedeutung erlangt haben.

Es folgen Ausführungen zu den verschiedenen Möglichkeiten der Kombination von Kraft- und Lageregelung - neben der Möglichkeit einer passiven Nachgiebigkeit des Roboters 3 verschiedene aktive Regelungen.

Zum Abschluss wird eine Projektarbeit der Universität Kaiserslautern vorgestellt, in der an einem käuflich zu erwerbenden Standard-Roboter eine Hybridregelung implementiert wurde.

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