

Off-line Programming Industrial Robots Based in the Information Extracted From Neutral Files Generated by the Commercial CAD Tools

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1. Introduction

In order for a robotic manipulator to perform useful work, it must be programmed to accomplish the desired task or motion cycle. Nowadays industrial robots generally require a tremendous amount of programming to make them useful. Their controllers are very sophisticated, the commercial robot programming environments are typically closed systems and the programming languages varies from manufacturer to manufacturer. Despite the great evolution of the industrial robots controllers, in the majority of the industrial applications, the robot programming is made, using one of the following ways:

- Manual on-line programming;
- Off-line programming;

Manual on-line programming refers to physically teaching a robot the required trajectory, through interaction with teach pendant or other similar device (Lee & ElMaraghy, 1990). This programming kind presents the following disadvantages: very slow, it needs that the robot is available, difficulty in the handling of equipments, need some practice in the language used by the robot, and technical knowledge to understand the operation of the equipment. These disadvantages are very expensive in the industry because the productive process needs to stop for a long time.

One simple approach to solve some disadvantages described above is the Off-line programming environments. These environments are based in graphical simulation platforms, in which the programming and execution process are shown using models of the real objects. Consequently, the robot programmer has to learn only the simulation language and not any of the robot programming languages. Other benefits in off-line programming environments include libraries of pre-defined high-level commands for certain types of applications, such as painting or welding, and the possibility to assess the kinematics feasibility of a move, thus enabling the user to plan collision-free paths. The simulation may also be used to determine the cycle time for a sequence of movements. These environments usually provide a set of primitives commonly used by various robots, and produce a sequence of robot manipulator language primitives such as "move" or "open gripper" that are then downloaded in the respective robot controllers.

Off Line Programming Of Industrial Robots

He Lyu



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Offline Programming for Industrial Robots with CAD/CAM Assistance Ron Speed, Society of Manufacturing Engineers, 1987

Offline Programming of Industrial Robots Using Interactive Computer Graphics Donald F.

Stephancic, 1982 **Off-line Programming of Industrial Robots** IFIP WG 5.3/IFAC Working Conference on Off-Line, 1987

Off-line Programming of Industrial Robots Alfred Storr, J. F. McWaters, 1987 Industrial robots are now being more readily included into highly integrated expensive manufacturing systems The development of off line teaching methods has thus become increasingly important if costly on line programming time is to be avoided This combined with the fact that the programming aspect now forms one of the major bottlenecks delaying the expansion of robot applications makes this book most timely in its attempt to offer solutions to the problem The comparison of methods and experiments contained in this volume will be of help in establishing guidelines for future industrial use of robots Programming strategies are examined as are assembly applications simulation programming aids and programming for a CIM environment A number of examples are included illustrating the current state of off line techniques **Simulation and Calibration for Off-line Programming of Industrial Robots** Uday Sakharam Pathre, Society of Manufacturing Engineers, Robotics International of SME., 1994

Industrial Robotics, 2004 **Handbook of Industrial Robotics** Shimon Y. Nof, 1999-03-02 About the Handbook of Industrial Robotics Second Edition Once again the Handbook of Industrial Robotics in its Second Edition explains the good ideas and knowledge that are needed for solutions Christopher B Galvin Chief Executive Officer Motorola Inc The material covered in this Handbook reflects the new generation of robotics developments It is a powerful educational resource for students engineers and managers written by a leading team of robotics experts Yukio Hasegawa Professor Emeritus Waseda University Japan The Second Edition of the Handbook of Industrial Robotics organizes and systematizes the current expertise of industrial robotics and its forthcoming capabilities These efforts are critical to solve the underlying problems of industry This continuation is a source of power I believe this Handbook will stimulate those who are concerned with industrial robots and motivate them to be great contributors to the progress of industrial robotics Hiroshi Okuda President Toyota Motor Corporation This Handbook describes very well the available and emerging robotics capabilities It is a most comprehensive guide including valuable information for both the providers and consumers of creative robotics applications Donald A Vincent Executive Vice President Robotic Industries Association 120 leading experts from twelve countries have participated in creating this Second Edition of the Handbook of Industrial Robotics Of its 66 chapters 33 are new covering important new topics in the theory design control and applications of robotics Other key features include a larger glossary of robotics terminology with over 800 terms and a CD ROM that vividly conveys the colorful motions and intelligence of robotics With contributions from the most prominent names in robotics worldwide the Handbook remains the essential resource on all aspects of this complex subject **Industrial Robot Offline Programming System Development and Its Applications**

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 Industrial Robotics Handbook V. Daniel Hunt,1983 Presents information obtained from a variety of knowledgeable
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Table of Contents Off Line Programming Of Industrial Robots

1. Understanding the eBook Off Line Programming Of Industrial Robots
 - The Rise of Digital Reading Off Line Programming Of Industrial Robots
 - Advantages of eBooks Over Traditional Books
2. Identifying Off Line Programming Of Industrial Robots
 - Exploring Different Genres
 - Considering Fiction vs. Non-Fiction
 - Determining Your Reading Goals
3. Choosing the Right eBook Platform
 - Popular eBook Platforms
 - Features to Look for in an Off Line Programming Of Industrial Robots
 - User-Friendly Interface
4. Exploring eBook Recommendations from Off Line Programming Of Industrial Robots
 - Personalized Recommendations
 - Off Line Programming Of Industrial Robots User Reviews and Ratings
 - Off Line Programming Of Industrial Robots and Bestseller Lists
5. Accessing Off Line Programming Of Industrial Robots Free and Paid eBooks
 - Off Line Programming Of Industrial Robots Public Domain eBooks
 - Off Line Programming Of Industrial Robots eBook Subscription Services
 - Off Line Programming Of Industrial Robots Budget-Friendly Options
6. Navigating Off Line Programming Of Industrial Robots eBook Formats

- ePub, PDF, MOBI, and More
 - Off Line Programming Of Industrial Robots Compatibility with Devices
 - Off Line Programming Of Industrial Robots Enhanced eBook Features
7. Enhancing Your Reading Experience
 - Adjustable Fonts and Text Sizes of Off Line Programming Of Industrial Robots
 - Highlighting and Note-Taking Off Line Programming Of Industrial Robots
 - Interactive Elements Off Line Programming Of Industrial Robots
 8. Staying Engaged with Off Line Programming Of Industrial Robots
 - Joining Online Reading Communities
 - Participating in Virtual Book Clubs
 - Following Authors and Publishers Off Line Programming Of Industrial Robots
 9. Balancing eBooks and Physical Books Off Line Programming Of Industrial Robots
 - Benefits of a Digital Library
 - Creating a Diverse Reading Collection Off Line Programming Of Industrial Robots
 10. Overcoming Reading Challenges
 - Dealing with Digital Eye Strain
 - Minimizing Distractions
 - Managing Screen Time
 11. Cultivating a Reading Routine Off Line Programming Of Industrial Robots
 - Setting Reading Goals Off Line Programming Of Industrial Robots
 - Carving Out Dedicated Reading Time
 12. Sourcing Reliable Information of Off Line Programming Of Industrial Robots
 - Fact-Checking eBook Content of Off Line Programming Of Industrial Robots
 - Distinguishing Credible Sources
 13. Promoting Lifelong Learning
 - Utilizing eBooks for Skill Development
 - Exploring Educational eBooks
 14. Embracing eBook Trends
 - Integration of Multimedia Elements
 - Interactive and Gamified eBooks

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