Improved end-effector trajectory control during arc and spline interpolations.

The trajectory does not change even if the operating speed changes, so there is no need for adjustment after teaching.

Realization of higher precision and shorter adjustment time for applications such as sealant application, cutting, etc.
Higher Accuracy of Absolute Position and Trajectory

Real-time correction of tracking errors and arm deformation to achieve higher accuracy.

Significantly improved trajectory accuracy around corners compared to conventional methods.

Applicable to any trajectory, including three-dimensional shapes.
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Applicable to any trajectory, including three-dimensional shapes.

Reduces trajectory errors by up to 80%
Automatic adjustment of robot kinematic geometric parameter model by using measurement data of tool tip position.

Reduces the absolute position error to less than 1/10th of compared with before adjustment. Reduces the absolute positioning error of the tool to less than 1/10th of conventional methods.

There is no need to teach robot manually for matching an actual path with the command path. Trajectories created with CAD data do not need to be corrected in the real environment, reducing teaching time.