

Abstract Details

Title: The Arm Equation and Reliability of 6-DOF KUKA Robot

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Abstract: In this paper the arm equation of 6-axes articulated KUKA robot [KR-16] is derived using Denavit-Hartenberg algorithm. Given an explicit task to be executed, a robot might be used to find the probability of success or reliability. Here, an experimental set up has been established and reliability is evaluated from experimental data. Moreover, a relationship between reliability and repeatability of robot is established.

Keywords: Forward Kinematics, KUKA Robot, Reliability.