



Development of vertical articulated robot deburring system by Using sensor feedback

Hiroki Kakoi¹, Kiyoshi Yanagihara^{2*}, Koji Akashi² and Kensuke Tsuchiya³

¹ Department of Creative Engineering, National Institute of Technology, Ariake College, 150 Higashihagio-Machi, Fukuoka, 836-8585, Japan

² Faculty of Creative Engineering, National Institute of Technology, Ariake College, 150 Higashihagio-Machi, Fukuoka, 836-8585, Japan

³ Institute of Industrial Science, The University of Tokyo, Komaba4-6-1 Megur-ku, Tokyo, 153-8505, Japan

* Corresponding Author: kiyoshi@ariake-nct.ac.jp, Telephone Number: +81-944-53-8864

Abstract

Chronic shortage of skilled engineer and strong demand of customer for quality drive robotization of hand finishing process recently. This study is about Robotization of deburring by means of hand grinder which is one of hand finishing tools. Basically, teaching operation is selected for the programming of tool path of robotic arm in robotization of hand finishing process. However, vertical articulated robot equipped with various sensors is developed for the robotic deburring system in this study

Keywords: Deburring, Vertical multi-joint robot, Grinding, Fixed abrasive, Sensor feed-back