ABSTRACT

Development of Deburring System using Force/Torque Sensor and a 6 DOF Robot

In recent years, the need of robotic deburring system for manufactured parts has been increased, but a few robotic deburring systems are applied in engineering fields with only passive end effectors. In this paper, an active end effector based force control system for robotic deburring is successfully implemented using a 6 DOF robot and force/torque sensor. This implemented system gives a new possibility of precision deburring by compensating robot oscillation and fixturing error of machined parts relative to the robot.

Key words : deburring system, force control, robot, F/T sensor

96405-507