

Übungen zum Praktikum Control of Robot Manipulators

Controlling the real robot

1. Port the homing command that you implemented for the simulator to the real robot. Make sure that the joints home one after another from the last to the first joint!
2. Port the motion sequence where you moved the joints from 0° to 90° and back to 0° (exercise 1b at exercise slide 2) to the real robot. Try to achieve this with
 - a position command that checks for the idle flag of the manipulator to know when to continue with the next joint.
 - a speed command that checks the current manipulator angle and the target angle to know, when to continue with the next joint. The speed should be reduced, as you come closer to the turning point at 90° .
 - a current command.