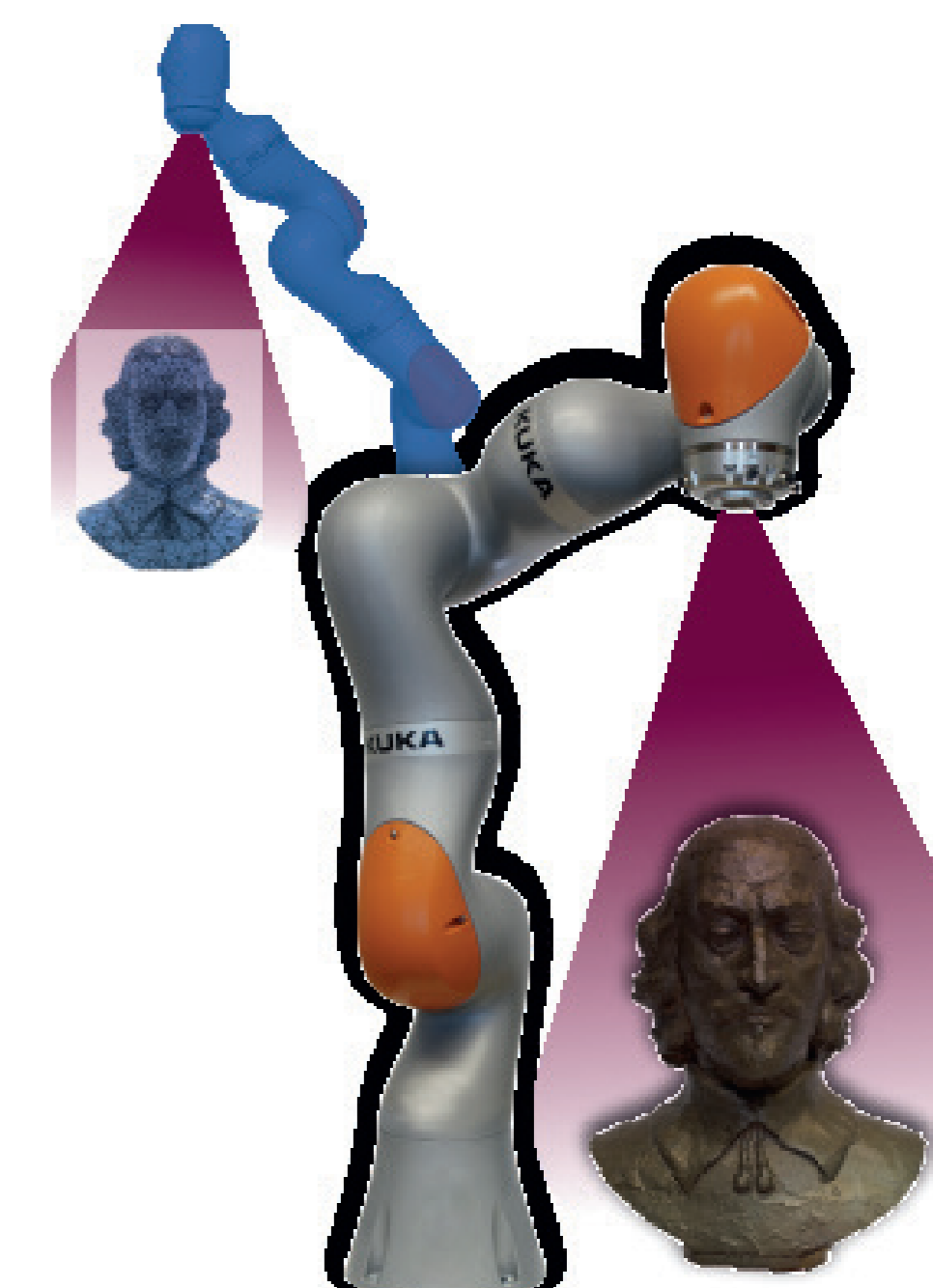




OPTIROB

Optimization of Robot Trajectories

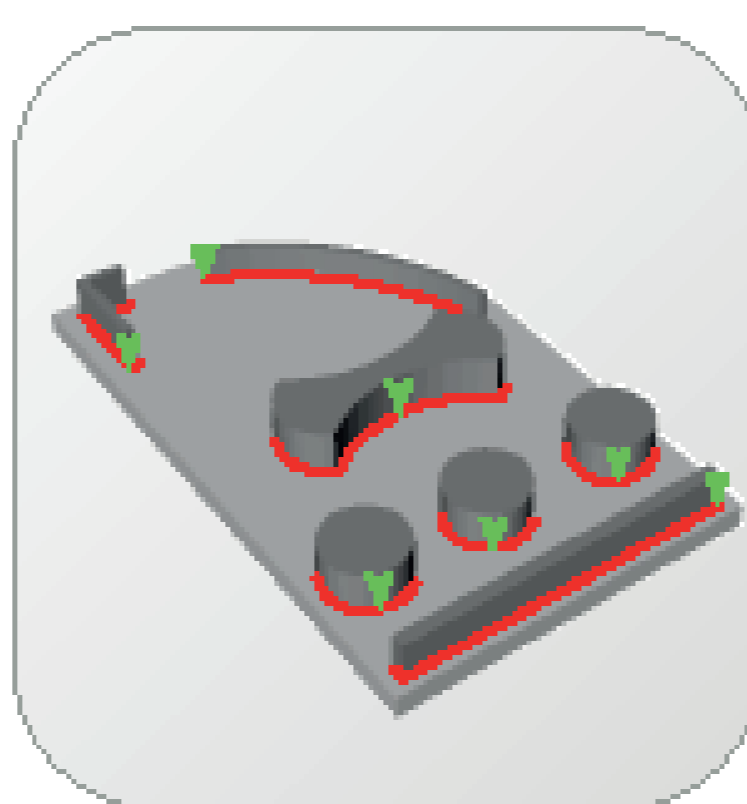


- ▶ minimize the cycle time and energy consumption of your application optimizing task sequences
- ▶ reduce the wear and jerk in the robot joints
- ▶ calculate optimal robot movements in the joint's space
- ▶ optimize the surface coverage with a minimal amount of material consumption

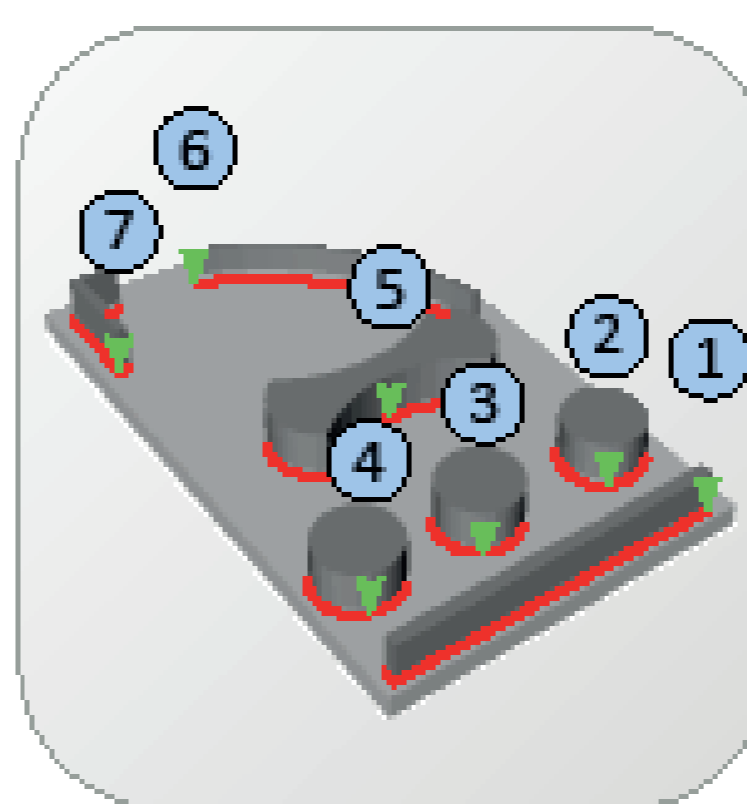
Task Sequence Optimization



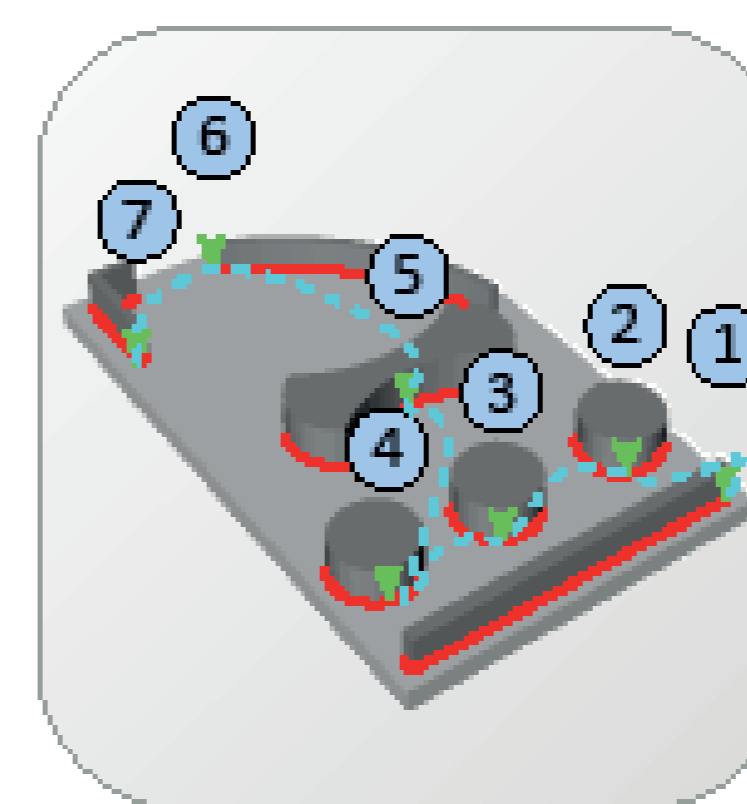
Effective Movements



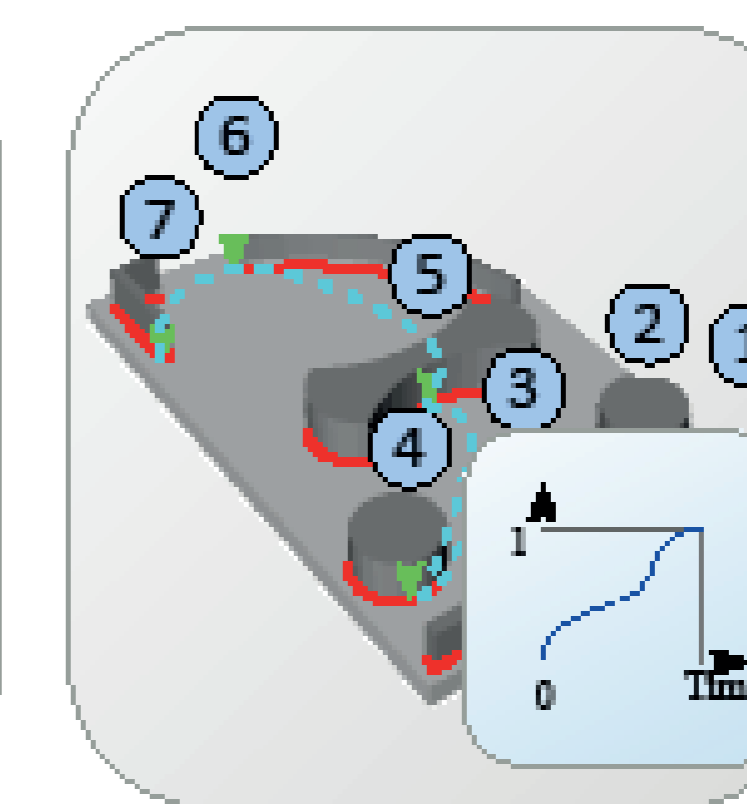
Entry and Exit Points



Sequencing



Collision-free Movements



Velocity Profile Definition

Coverage Path Planning



Surface Mesh



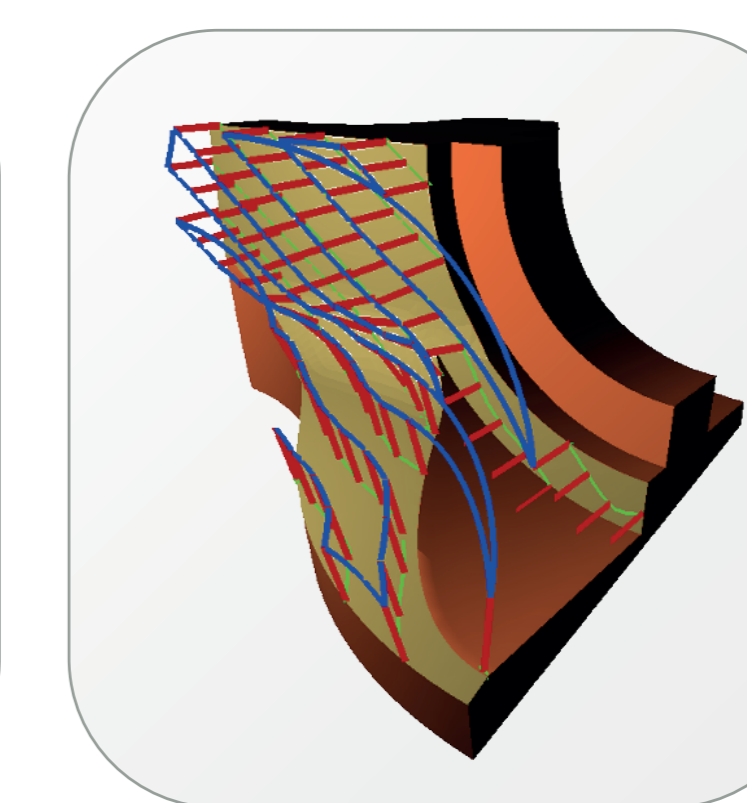
Sharp Edges Detection



Segmentation



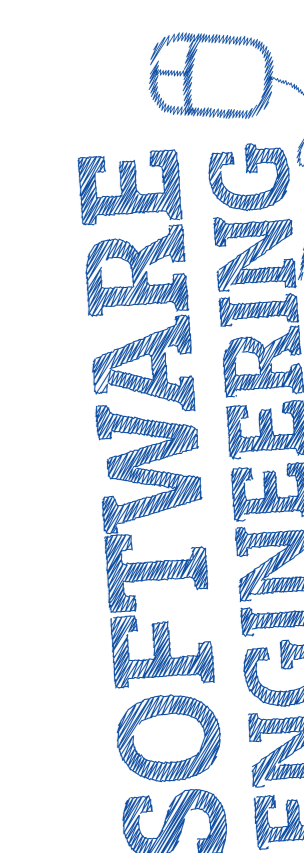
Offset Curves



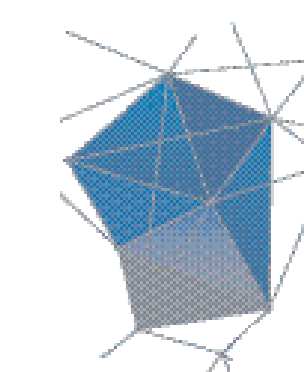
SLD & Path Planning



XITASO



cedemo
the future of engineering



KONTAKT

INFO

FÖRDERUNG der Messeteilnahme durch



Otto-von-Guericke-University Magdeburg · Faculty of Computer Science
 Institute for Intelligent Cooperating Systems
 Chair of Software Engineering · Prof. Dr. Frank Ortmeier
 Universitätsplatz 2 · 39106 Magdeburg
 Tel: +49 391 67 52804 · Fax: +49 391 67 12810
 frank.ortmeier@ovgu.de · <https://cse.cs.ovgu.de/>



EUROPÄISCHE UNION
ESIF
 Europäische Struktur- und
 Investitionsfonds