

6. CONCLUSIONS

The domestic industrial robots generally have a low positioning accuracy. What is worse, the robot industry is in want of feasible standards and detection instruments. This paper solves the defects of the existing conversion methods between the RCS and the LTCS, and then designs an end position detection method for industrial robots based on laser tracker. The method is simple to operate and widely applicable, eliminating the need for advanced measuring instruments or technical plans. The industrial robots whose positioning accuracy has been reduced through long-term wear could be effectively monitored by our method. Of course, our method also faces some limitations, namely, the relatively high measuring deviation and the complex data analysis. These limitations will be solved through error compensation in future research.

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