

Kinematic design calculation of industrial robot manipulator

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Abstract: This study focuses on calculating and designing the kinematics of industrial robot arms to meet the demand for optimizing operational performance in production lines. Through a combination of theoretical research and experimentation, the project develops an accurate dynamic model for each joint of the robot arm, thereby supporting automatic control and programming. The expected outcome is to provide an effective technical solution that contributes to improving production quality and productivity in the automation industry.

Keywords: robot arm, robot kinematics, automatic programming