Abstract

In recent decades, the robotic system is becoming more and more significant and this leads the humans to perform precarious tasks at secure distances. In this paper, we planned to improve the performance of robotic gear box. Like our human hand, the robot hands are utilized for performing various tasks. To facilitate the task, flexible robotic arms is necessary to improve the performance of robotic arm gear box. In existing research, only static parameters were considered to make the robotic arms as flexible but such parameter itself is not enough to obtain the optimized value for the gear box to perform. In order to attain the optimized value for the robotic arm gear box, we considered both dynamic and static parameters. By using such parameter values, the optimized value for the gear box is obtained, which result in better gear box performance. Thus, our proposed work fills the gap occurs in the existing works and this
paves the way for obtaining flexible robotic arms. Our result obtained by considering various parameters has shown better performance than the existing works.

References

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Index Terms

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Keywords

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