



3DSSC (3D Smart Sense and Control) Deliverable

Multimedia Report

*3D Smart Sensing and Flexible Task Programming for On-Line Trajectory Adaptation in
Fast Surface Treatment*

Karel Vander Elst (Flexible Robotic Solutions, Belgium)
Keivan Zavari (Flexible Robotic Solutions, Belgium)
Aertbeliën Erwin (KU Leuven University, Belgium)
De Schutter Joris (Flexible Robotic Solutions, Belgium)
Delforge Philippe (Flexible Robotic Solutions, Belgium)

1 Multimedia Report

The final phases of the project are carried out on an industrial robot (KUKA KR16).



Figure 1: Experimental setup using KUKA KR16.

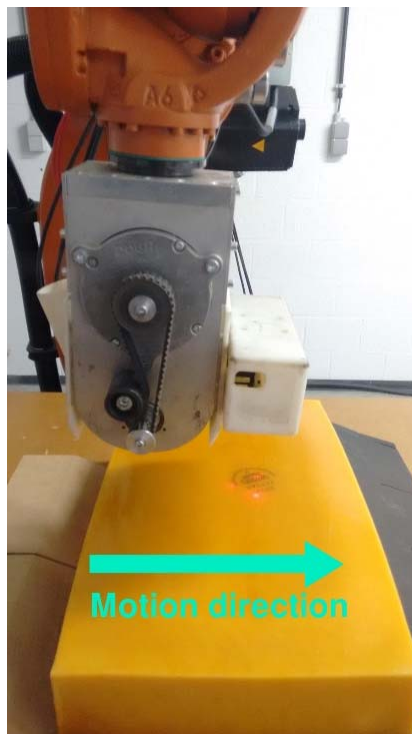


Figure 2: Experimental setup using KUKA KR16

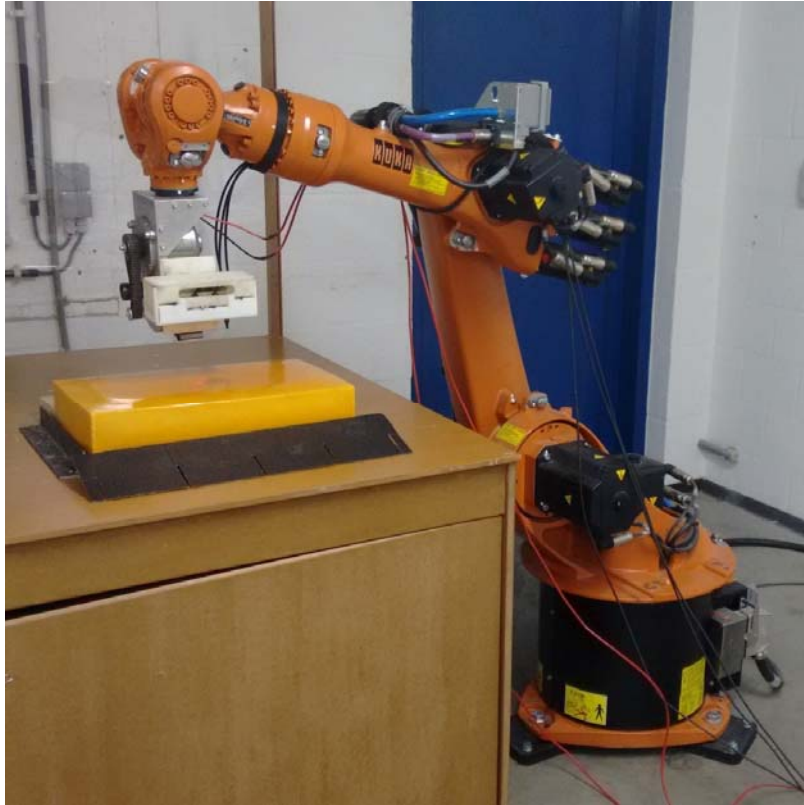


Figure 3: Experimental setup using KUKA KR16

The multimedia report is available at the following location:

<https://sway.com/qIE13OUI5YaVpc3v> , where the robot removes three strips of the top surface of a cheese block. A small view of this task is shown below:



Figure 4: The robot motion on the cheese block while removing the coating.