The project CoHRoS aimed at advancing the state-of-the-art in programming for highly redundant robot systems through developing a practical and robust method for assistive teaching.

It developed a method for structured user interaction to help programmers transfer their contextual knowledge about the application step by step to the robot. The project employed machine learning for generalizing this knowledge from examples.

The method was partially implemented and tested by application programmers as a prototype on a redundant welding robot manufactured by Cloos. The results showed that there is potential to enhance programming of complex applications for highly redundant robots can be significantly facilitated. However, the progress made was limited by the reduced effort invested in validation of the technology.

Background knowledge adopted from the Moftag experiment

* Learning approach used to learn both the end effector and the entire robot configurations, in four positions
* Kinesthetic teaching is by moving the robot around

Foreground gained in the project COHRoS

* The project relied in the work previously developed in the Moftag EHCORD experiment.
* Incremental improvements were made mainly in the aspects of interaction aiming to eliminate the part of the kinesthetic teaching and partially in robot learning.
* Comparison with commercial of the self-products was not considered.