

عنوان مقاله:

fuzzy model and adaptive control in intelligent welding robot

محل انتشار:

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تعداد صفحات اصل مقاله: 8

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خلاصه مقاله:

Quality of the multi-layer welding depends on the first layer welding . In order to get a high quality of the welding it is necessary to make a stable back bead and melting the base metals in narrow gap welding it is difficult to control the bead height and back bead simultaneously bu using conventional welding to improve this problem the author proposes a cooperative control of the welding equipments including the welding power source the electrode wire feeder and the welding robot i.e. the welding torch is not only oscillating on the groove but also moving back and forth .switch back wekding method . in thie forward process the are is given to the root edges to get a wide back bead

کلمات کلیدی:

robotic narrow gap welding,adaptive control, fuzzy model , numerical simulation

لینک ثابت مقاله در پایگاه سیویلیکا:

<https://civilica.com/doc/128488>

