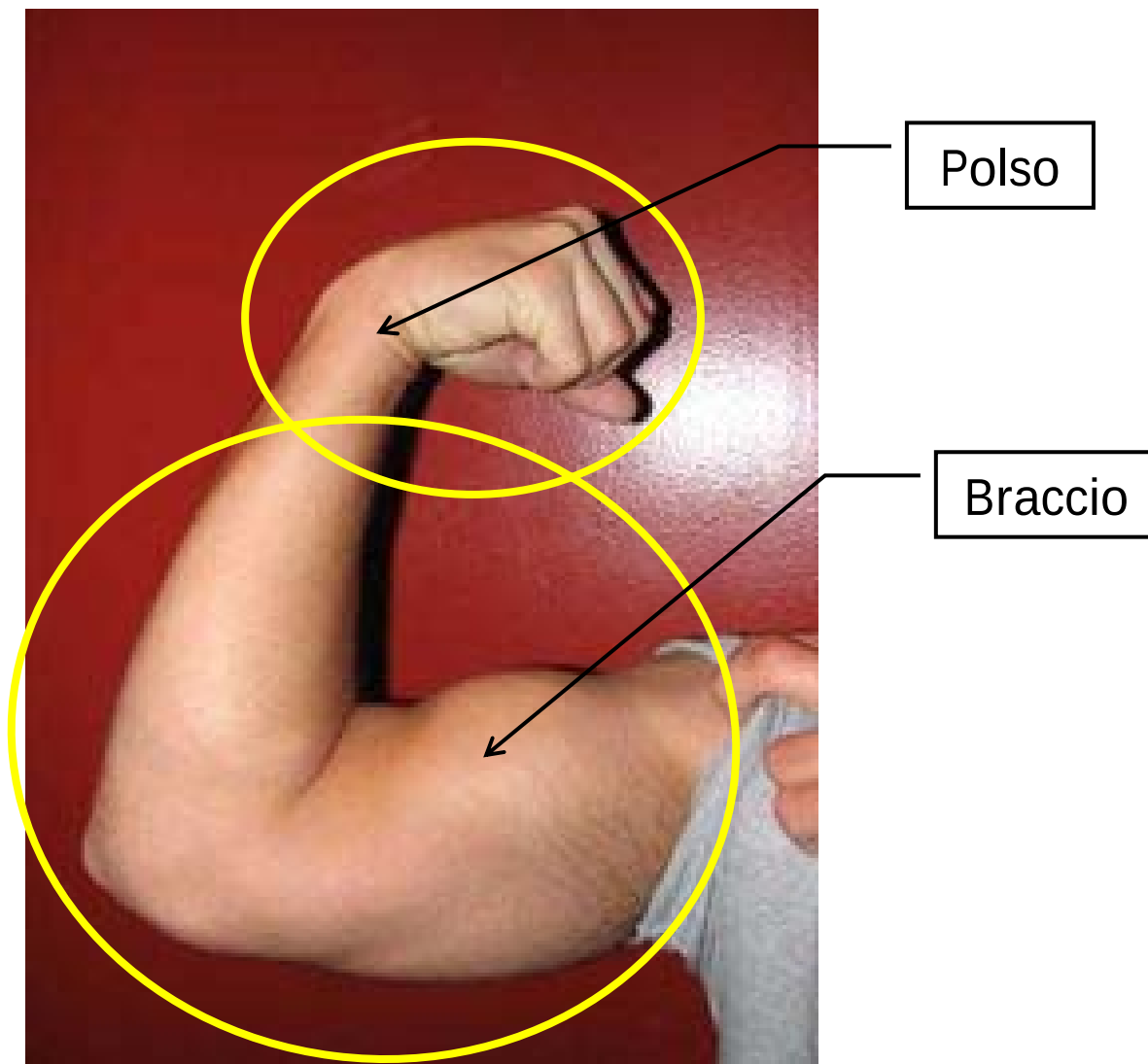
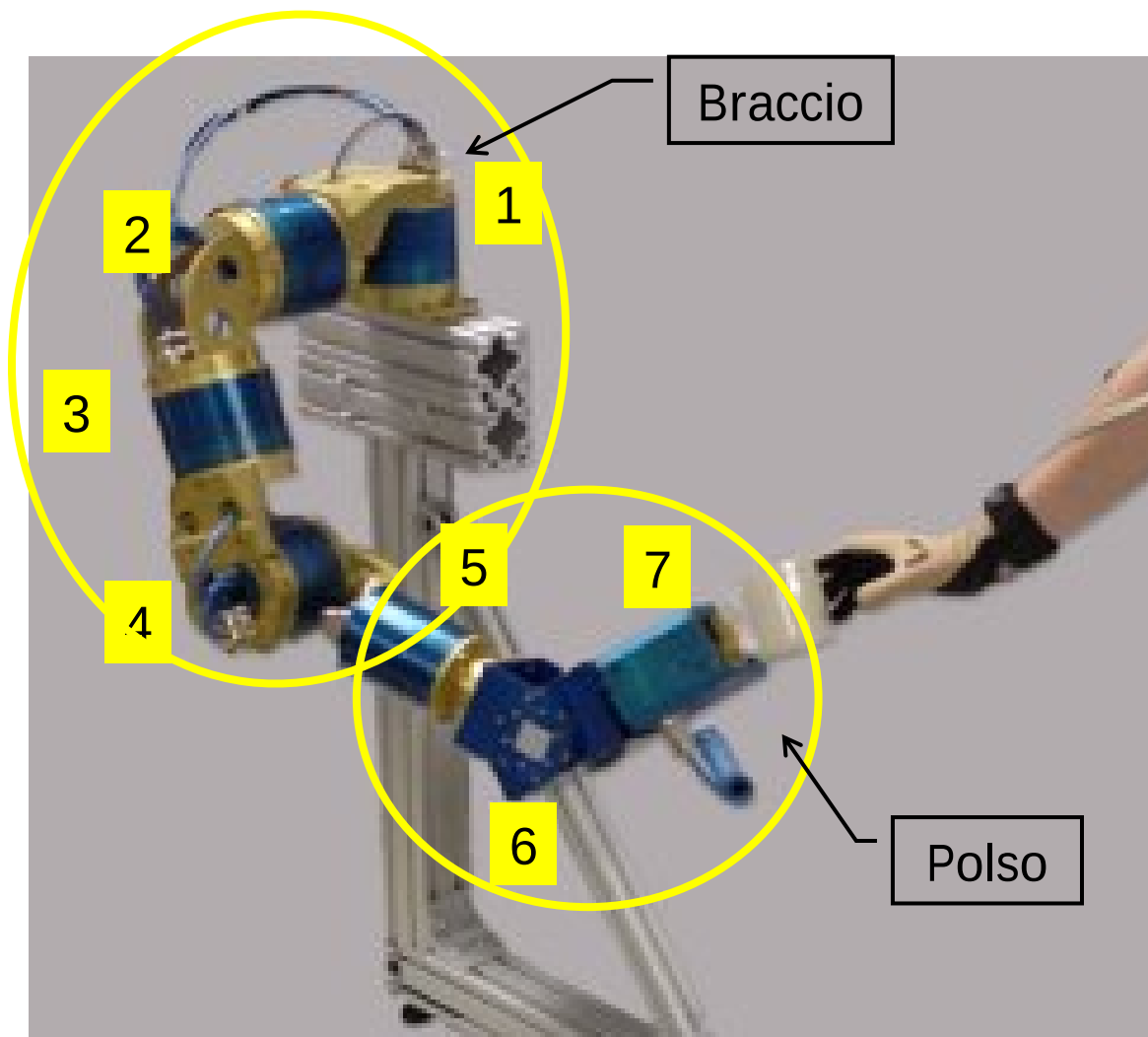


**Robot = Braccio + polso (arm + wrist)**



# GDL Braccio



# Tipi di braccio robotico

Il braccio si descrive con una sigla che indica il n.ro di giunti e il loro tipo

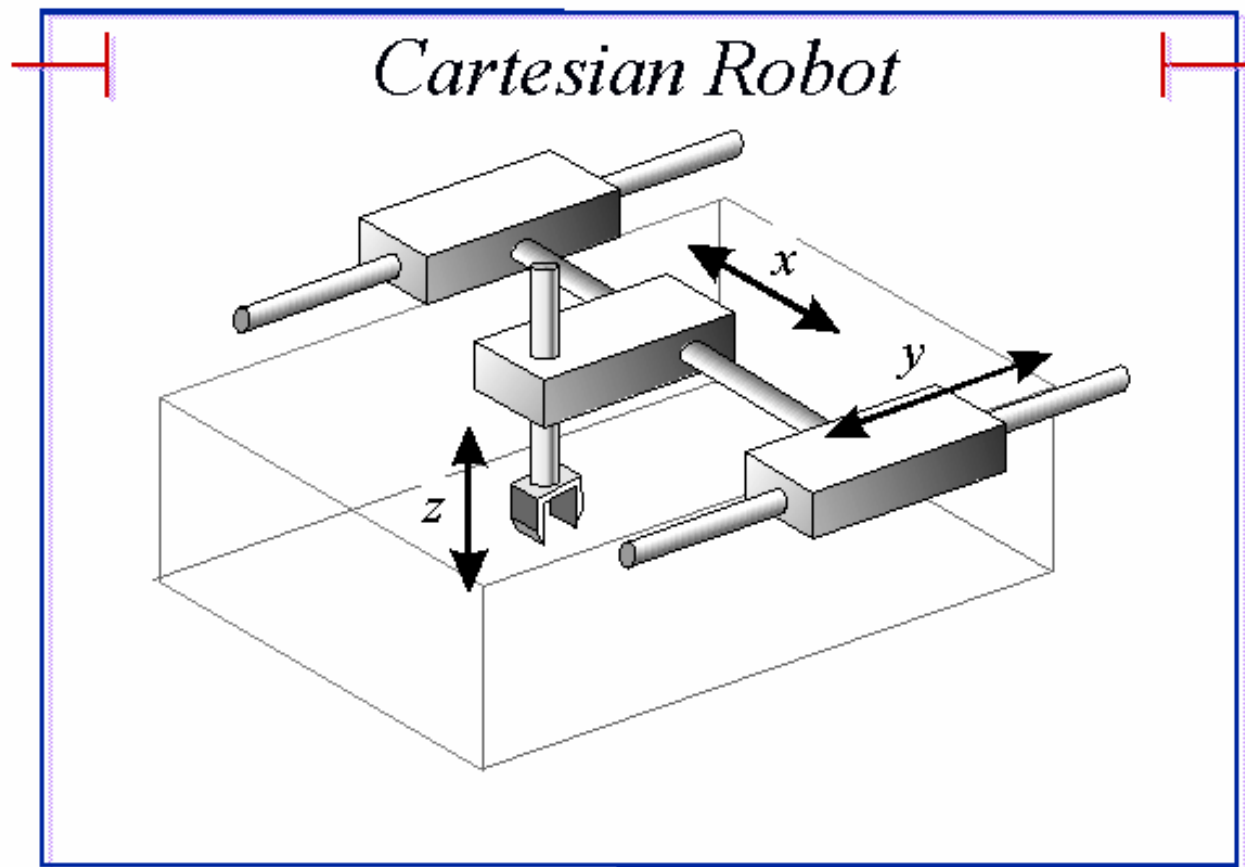
P = giunto prismatico

R = giunto rotoidale

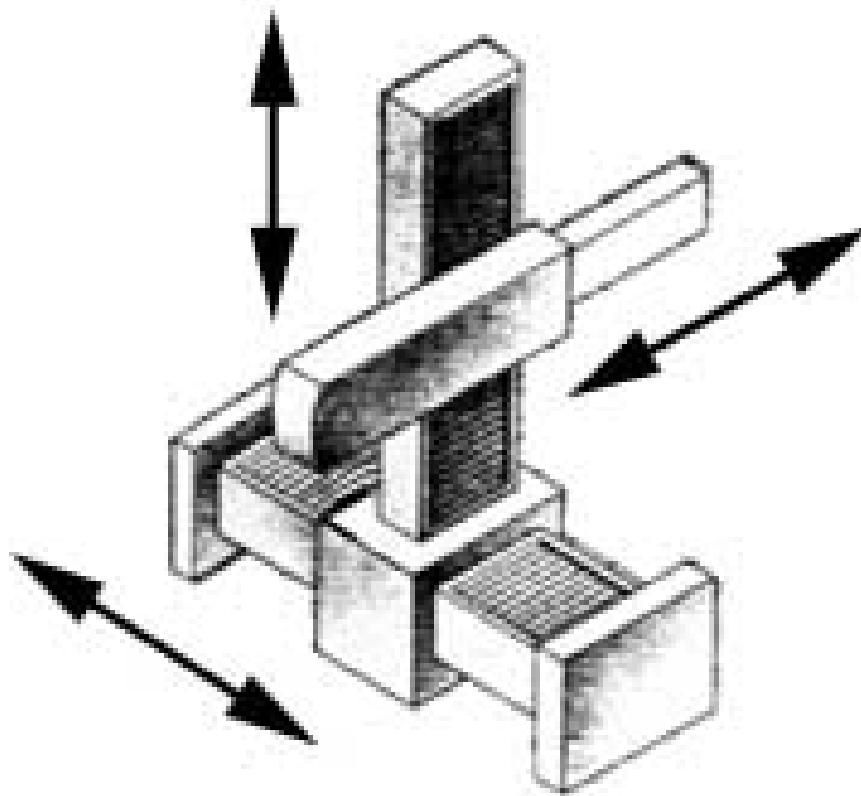
Tipi di robot

- Cartesiano  $\Rightarrow$  3P
- Cilindrico  $\Rightarrow$  2P-1R
- Polare o sferico  $\Rightarrow$  1P-2R
- SCARA 1P-2R;  
SCARA = Selective Compliance Assembly Robot Arm
- Articolato o antropomorfo  $\Rightarrow$  3R
- Struttura parallela

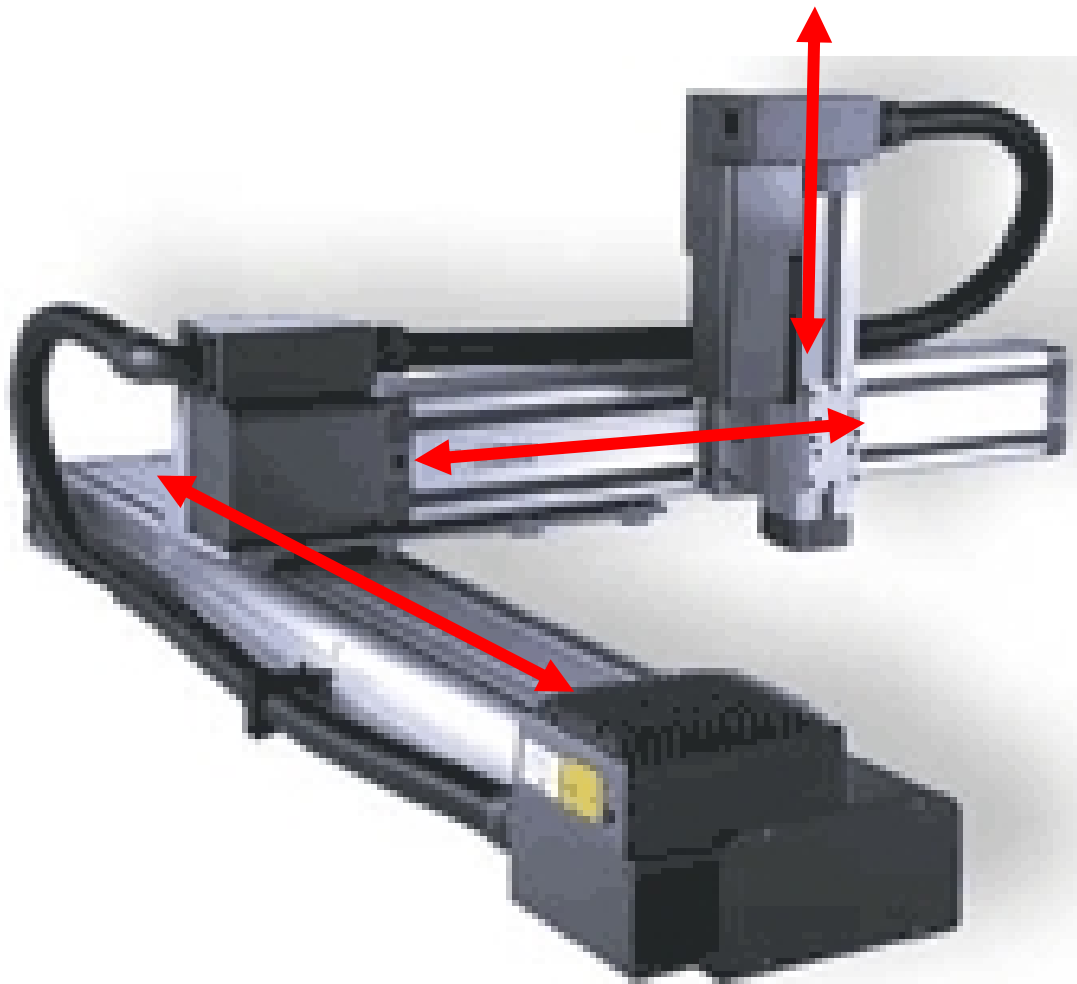
# CARTESIANO 1



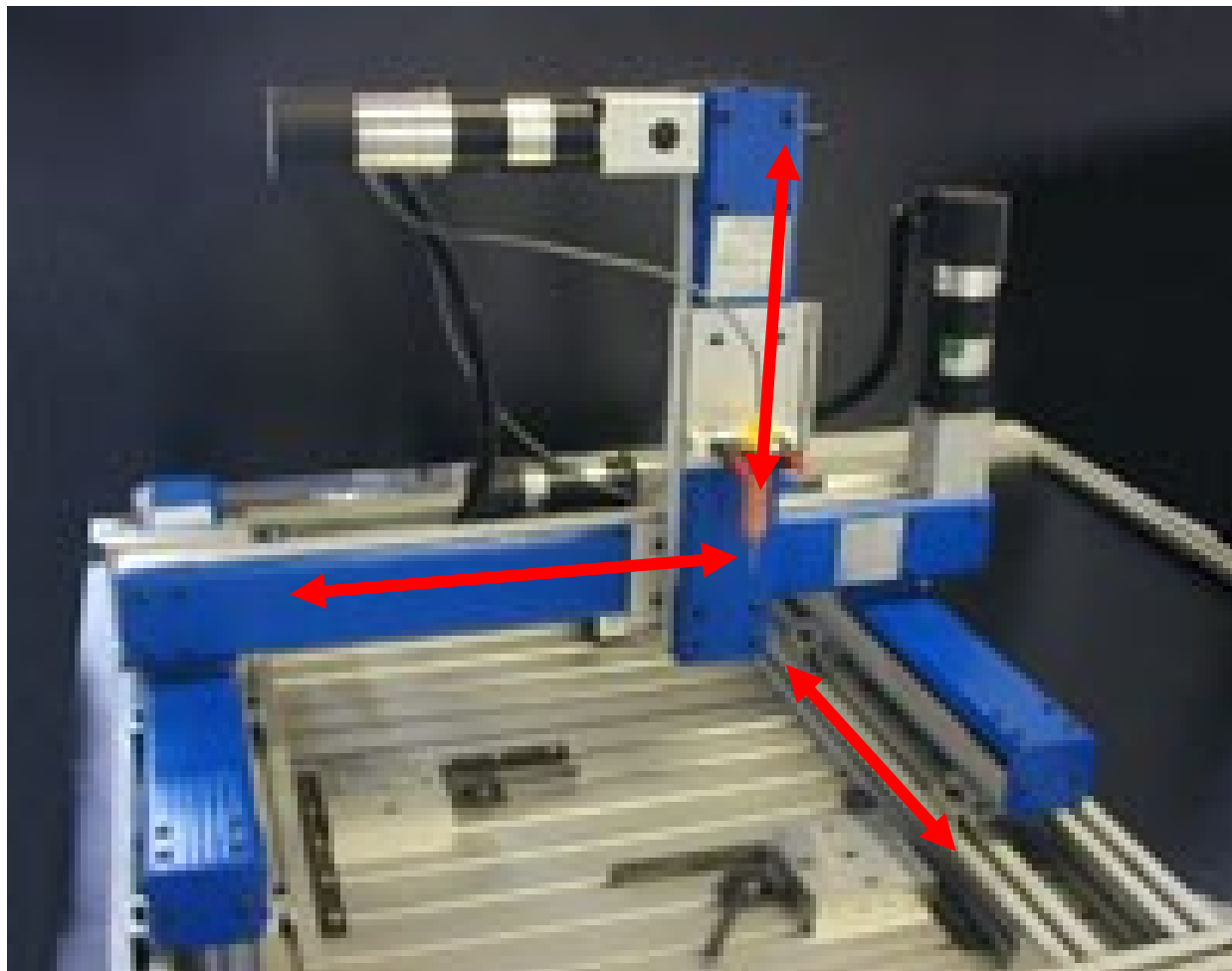
## CARTESIANO 2



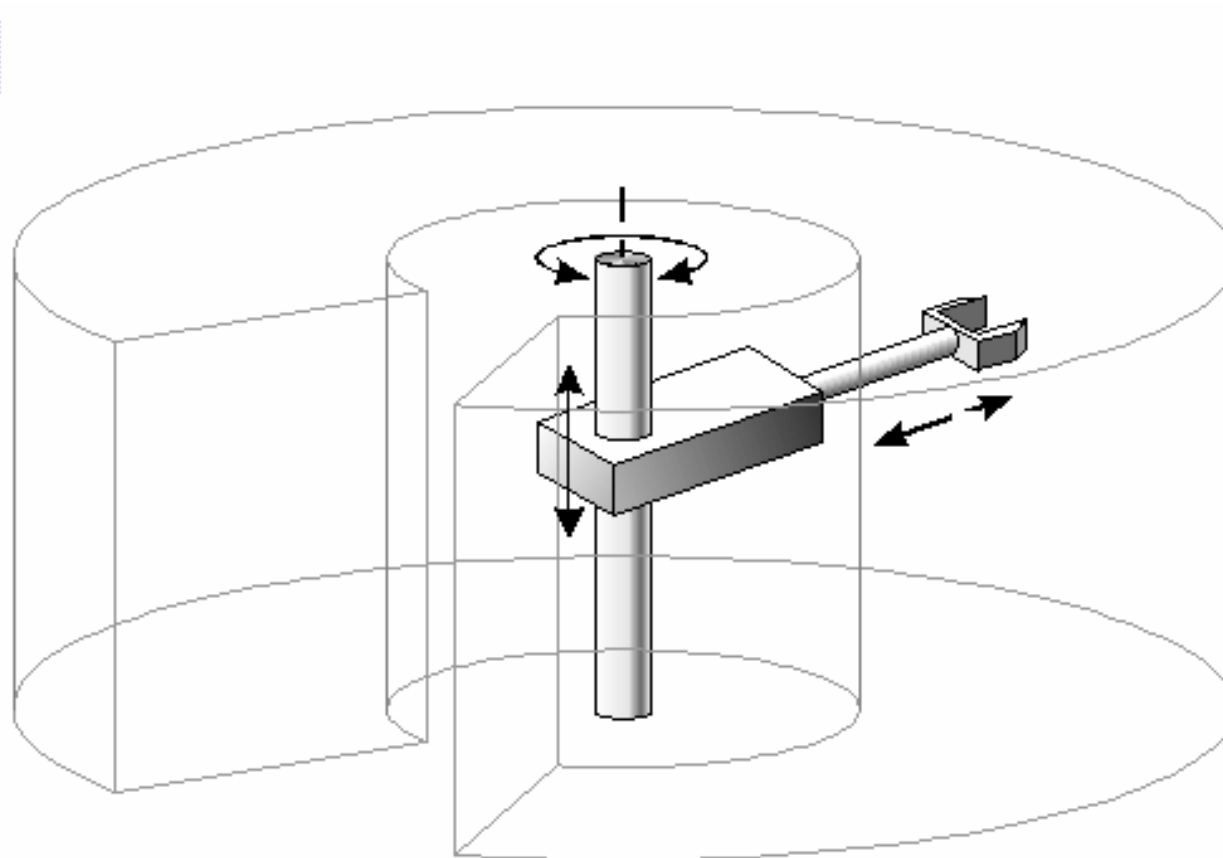
## CARTESIANO 3



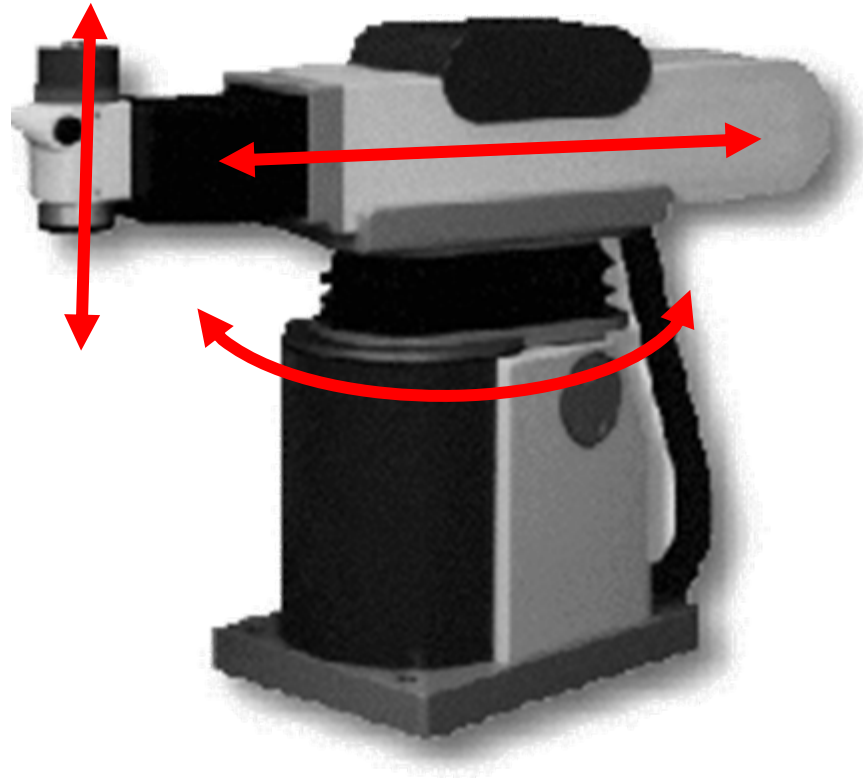
## CARTESIANO 4



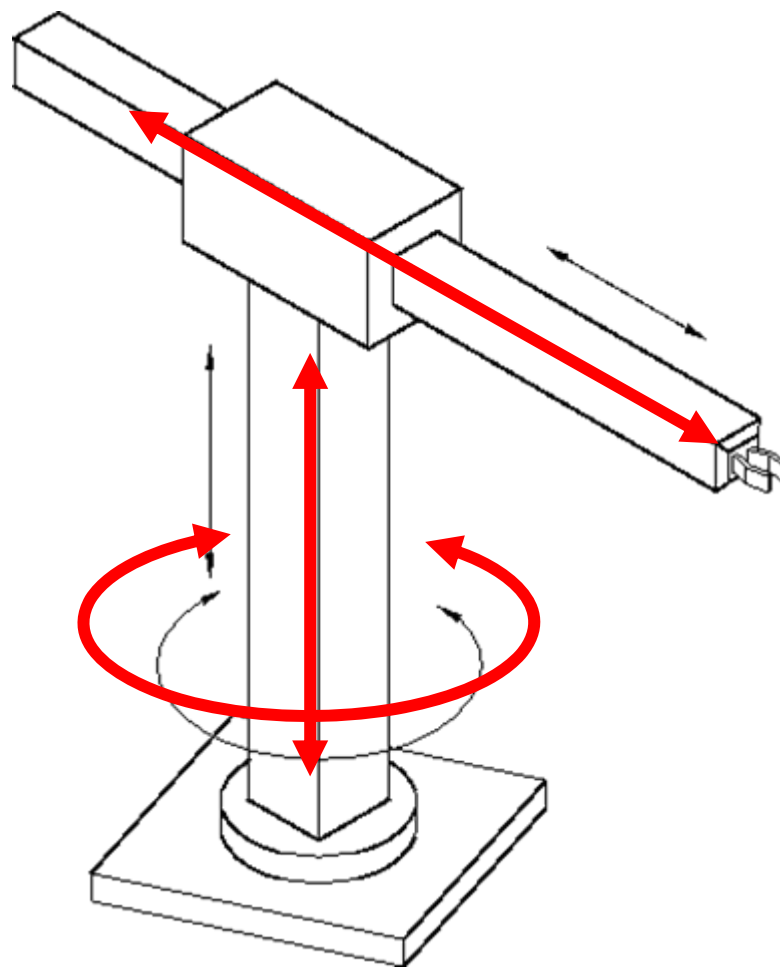
# CILINDRICO 1



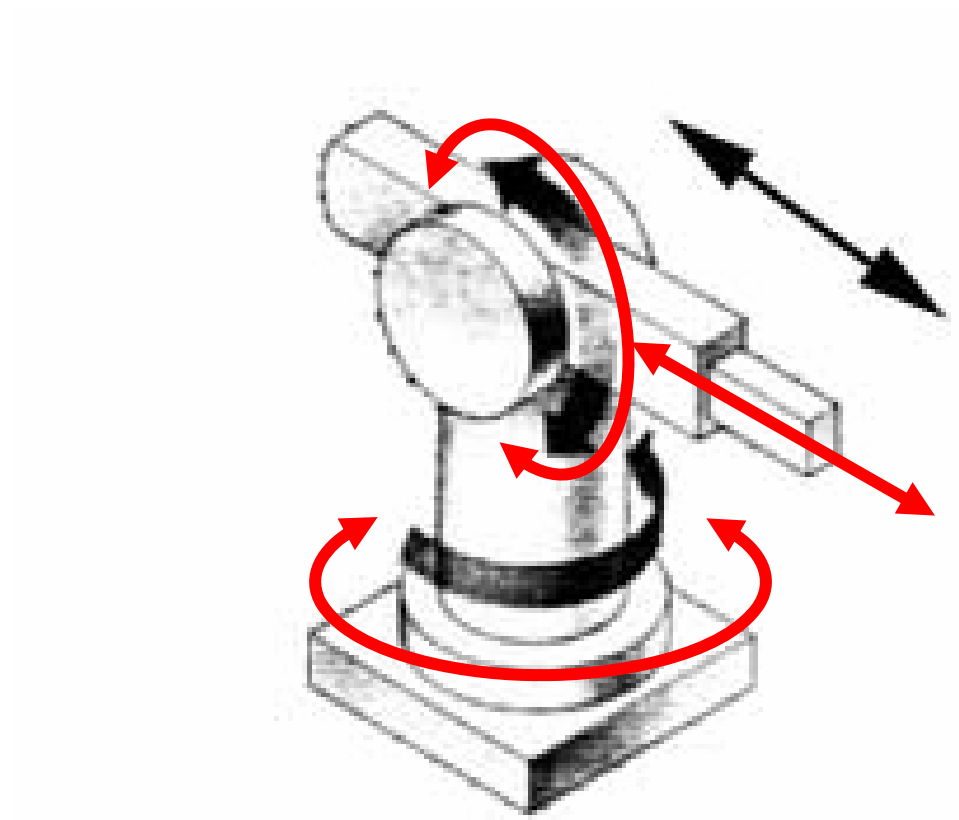
## CILINDRICO 2



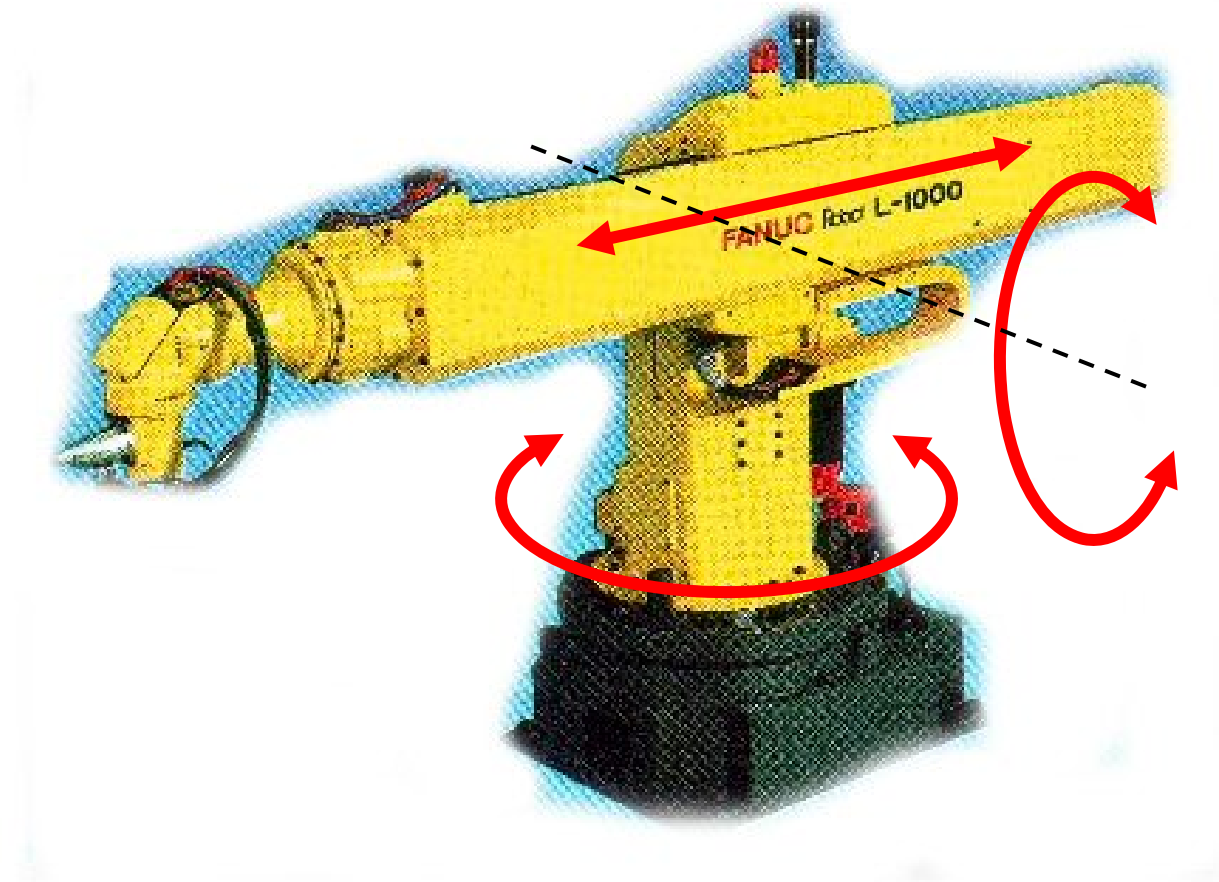
## CILINDRICO 3



# Polare 1



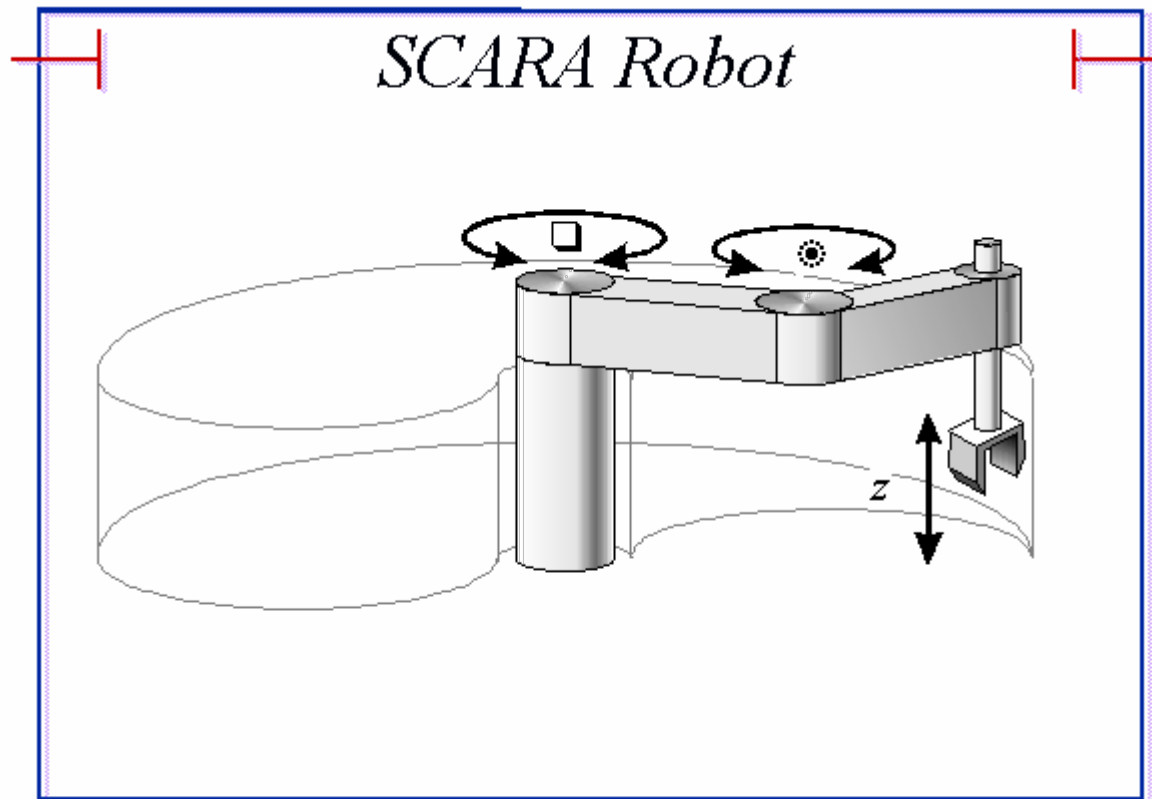
## Polare 2



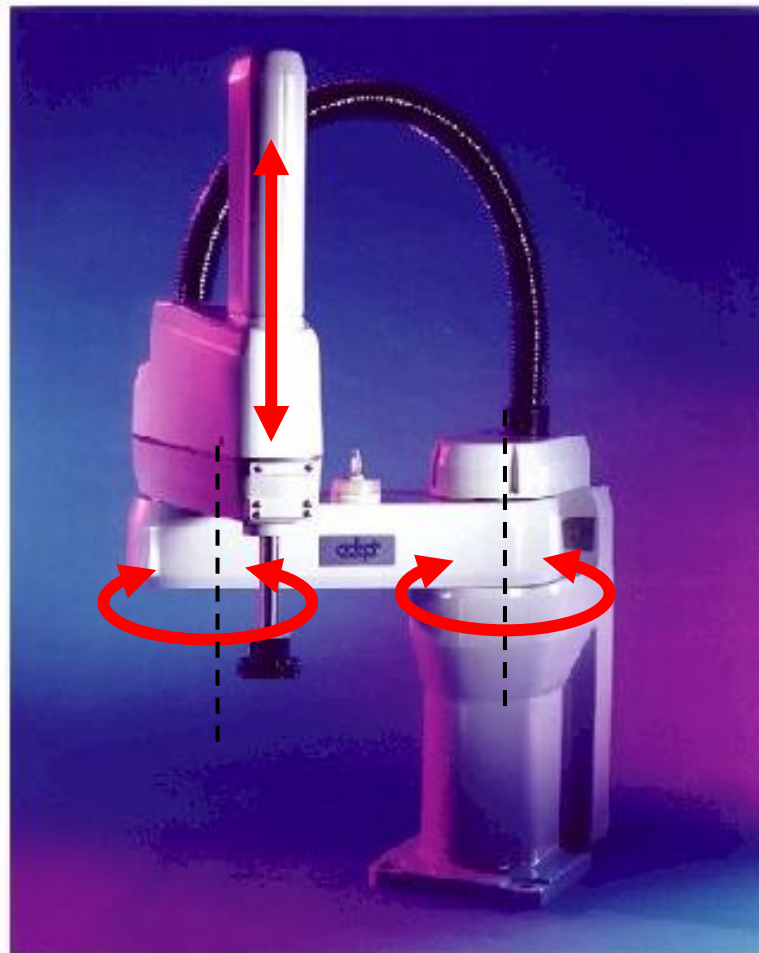
## Polare 3



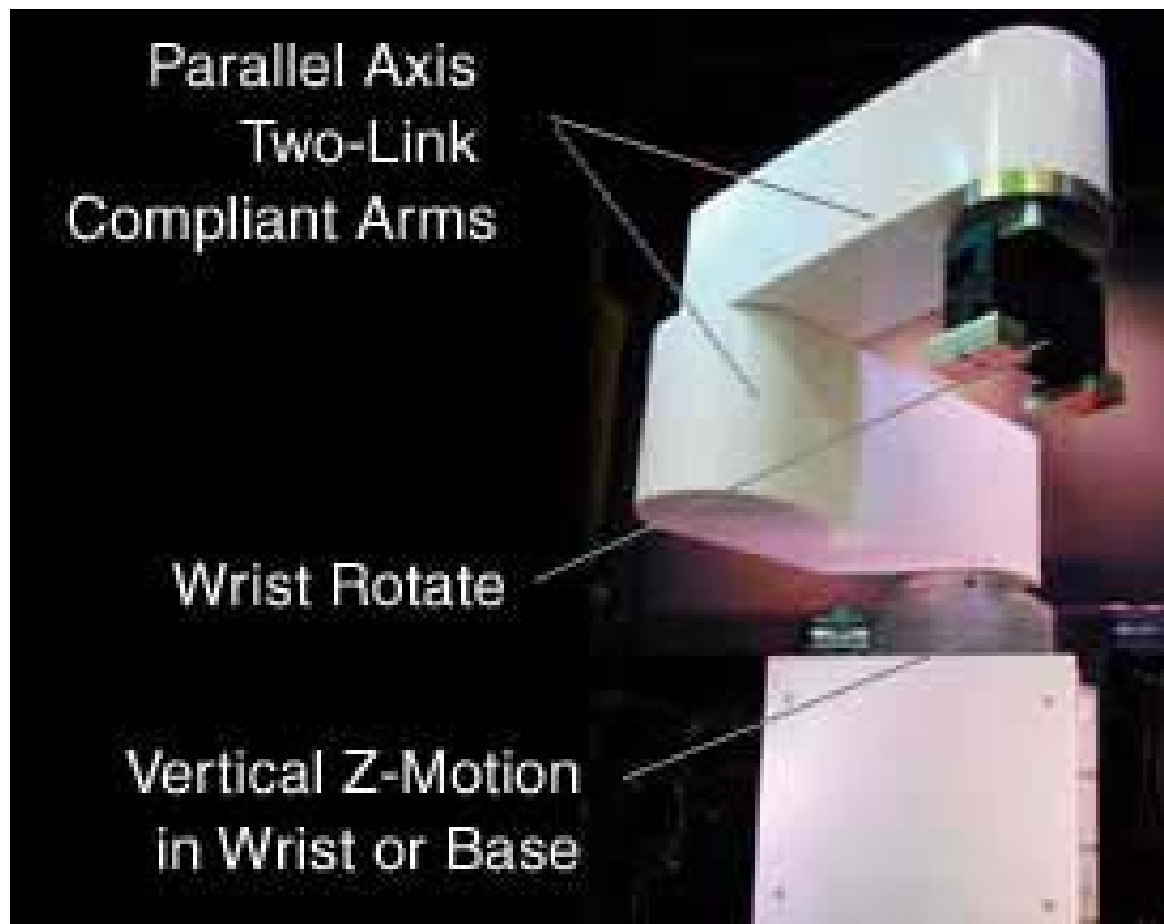
# SCARA 1



## SCARA 2



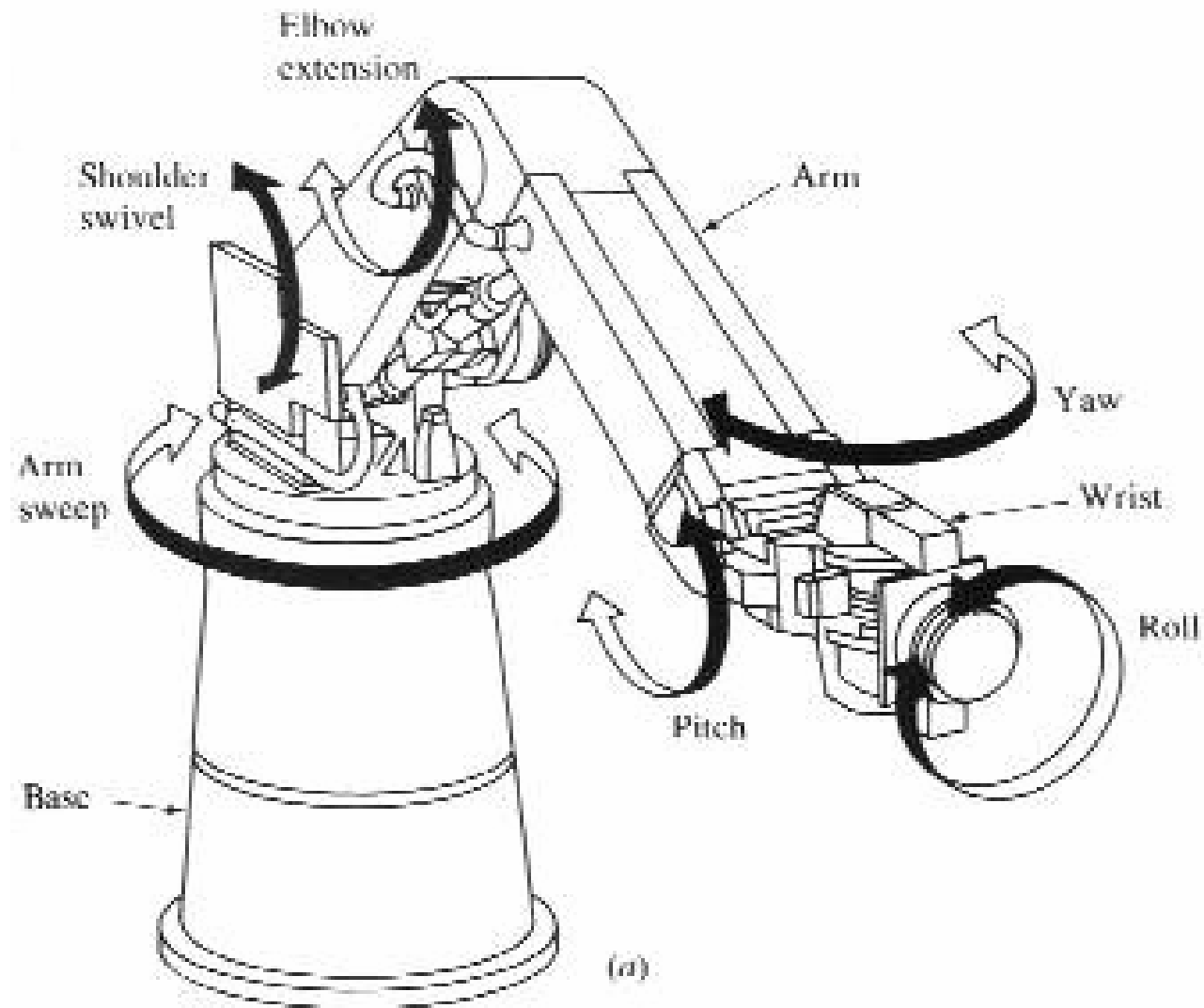
# SCARA 3



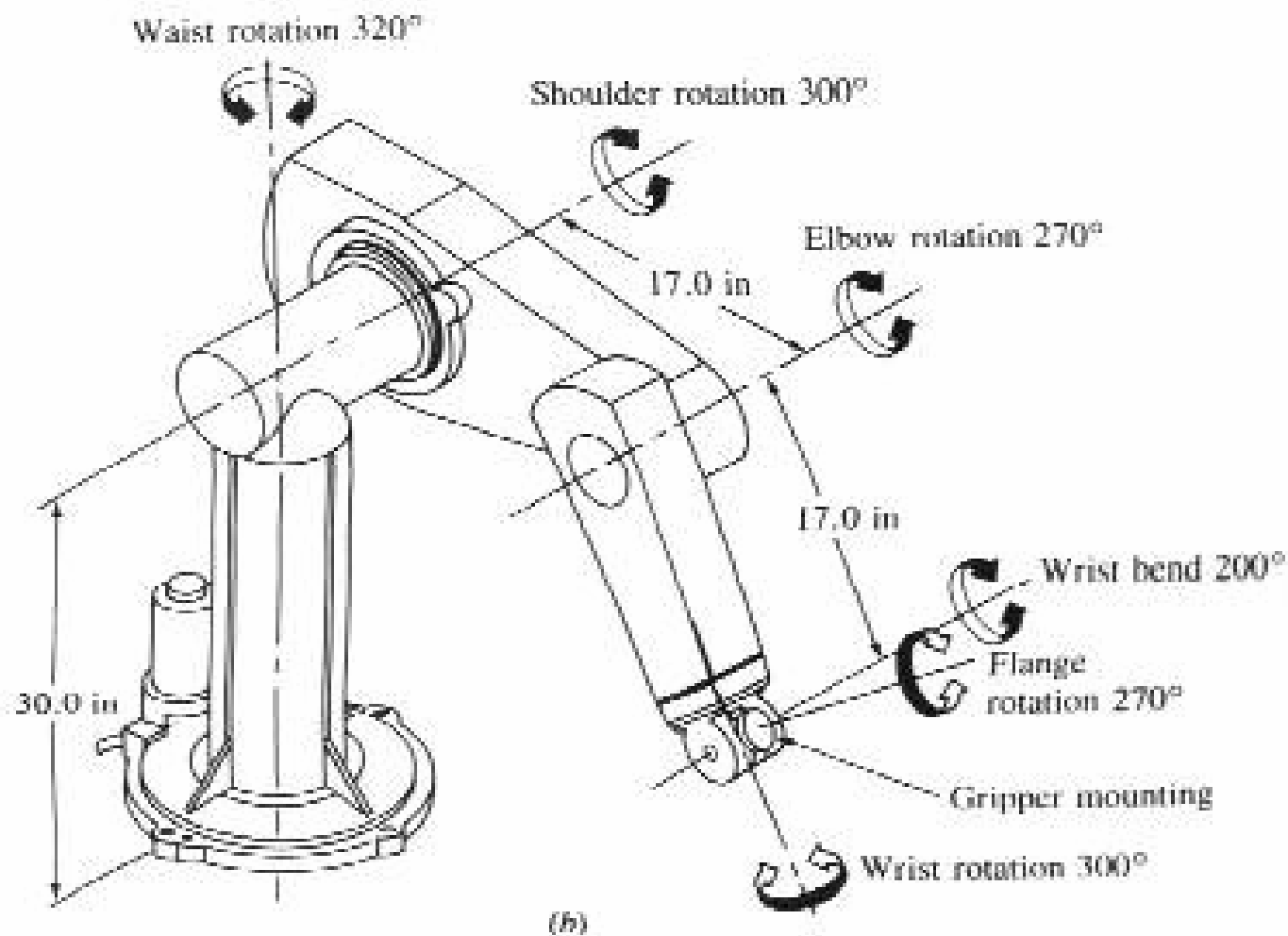
# Articolato 1



# Articolato 2



## Articolato 3



## Articolato 4



# Stuttura parallela

