

TOUCH SUBORDINATES MANAGEMENT OF INDUSTRIAL ROBOTS IMPROVING THE POSITIONAL ACCURACY OF THE MATHEMATICAL MODEL

R. SIDDIKOV

Teacher of the Kokand state pedagogical institute of the republic of Uzbekistan

ABSTRACT

In this paper were discussed the development of mathematical models and algorithms of optimal control of the functioning of industrial robots on the moving base to ensure the accuracy of the trajectory and positioning. Obtained equation of the operation of the industrial robot on a mobile base to perform complex spatial operations and on its basis the mathematical model of optimal control.

KEYWORDS: Industrial Robots, Motion Model, System of Optimal Control, Algorithm