

Sawang Panjun 2008: Motion Path Planning for Work Assembly Cooperative Dual Six Joints Robots. Master of Engineering (Industrial Engineering), Major Field: Industrial Engineering, Department of Industrial Engineering. Thesis Advisor: Mr.Chana Raksiri, D.Eng. 146 pages.

This paper describes a motion path planning for hole and shaft assembly cooperative dual six joints robots. The operation time is reduced and efficiency is increased flexible for various production processes. This study compared with result of tradition path planning which it can not make to assembly for hole and shaft. Because of during trajectory occurred collision for hole and shaft. The propose path planning divided position of trajectory that it have interval as same as. This path planning divided two steps. First step divided to quantity of collision position of end of joint and final step divided to different value between radius of hole and radius of shaft which it have maximum value not over rate of deviation value (R_{dif}). The operation time directed to quantity of interval for movement path. The study result is the propose path planning can reduce operation time and quantity of interval for motion path is 25.97 and 24.11 percent when compare with tradition path planning.

Student's signature

Thesis Advisor's signature

____ / ____ / ____