



# Kommunikationsmodell einer PC-basierten Robotersteuerung (German Edition)

*Michael Borchard*

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**Kommunikationsmodell einer PC-basierten Robotersteuerung (German Edition)** Michael Borchard  
Diplomarbeit aus dem Jahr 2001 im Fachbereich Informatik - Technische Informatik, Note: 1,0, Technische Universität Carolo-Wilhelmina zu Braunschweig (Institut für Robotik und Prozessinformatik), Sprache: Deutsch, Abstract: Gegenstand dieser Arbeit ist der Entwurf eines Kommunikationsmodells für eine PC-basierte Robotersteuerung und deren Implementierung.

Ausgehend von den Grundlagen der Kommunikation werden verschiedene Entwurfsalternativen erläutert. Die gewählte Alternative besteht in der Implementierung eines Object-Servers, der das Management der gesamten Steuerungskommunikation übernimmt. Als Schnittstelle zum Benutzer wird ein TCP/IP-Interface zur Verfügung gestellt, so dass die Robotersteuerung von beliebigen Computern in einem angeschlossenen Netzwerk in Betrieb genommen werden kann. Die nähere Betrachtung der durch den Object-Server und das TCP/IP-Interface disponiblen Funktionen bildet einen wesentlichen Teil dieser Arbeit.

Im letzten Teil der Arbeit werden dann die Modifikationen erläutert, die ausgehend von der vorhandenen Robotersteuerung vorgenommen werden mussten, um das gewählte Kommunikationskonzept zu realisieren. Die Beleuchtung einiger praktischer Aspekte der Benutzung des Roboters schließt die Arbeit ab.

Abstract

Objective of this thesis is a communication-model for a PC-based robot control system as well as its realisation.

Based on available communication-alternatives different implementation possibilities will be explained. The resulting Object-Server, which controls and manages the complete communication will be explained in more detail afterwards. An available user-communication-interface uses the TCP/IP-protocols to support connections to the „world“. Therefore the robot control system can be used by arbitrary computers in a common network.

Finally some modifications of the previously existing robot control system will be explained and some technical aspects of using the robot will be stated.

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