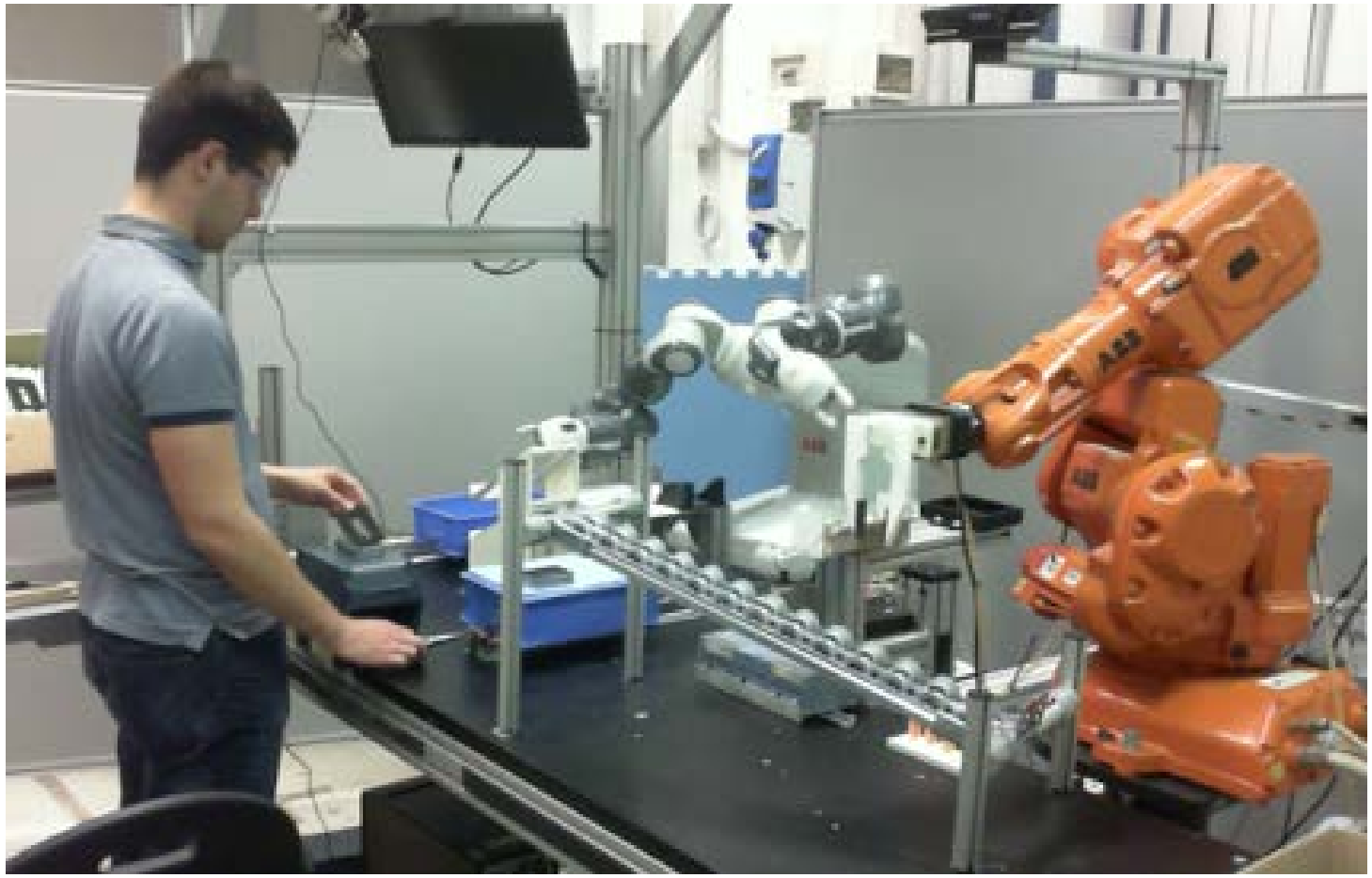
LECTURE 10
A case study

Andrea Zanchettin

Agenda

- Case study presentation
- Modelling, control and experiments

Case study presentation

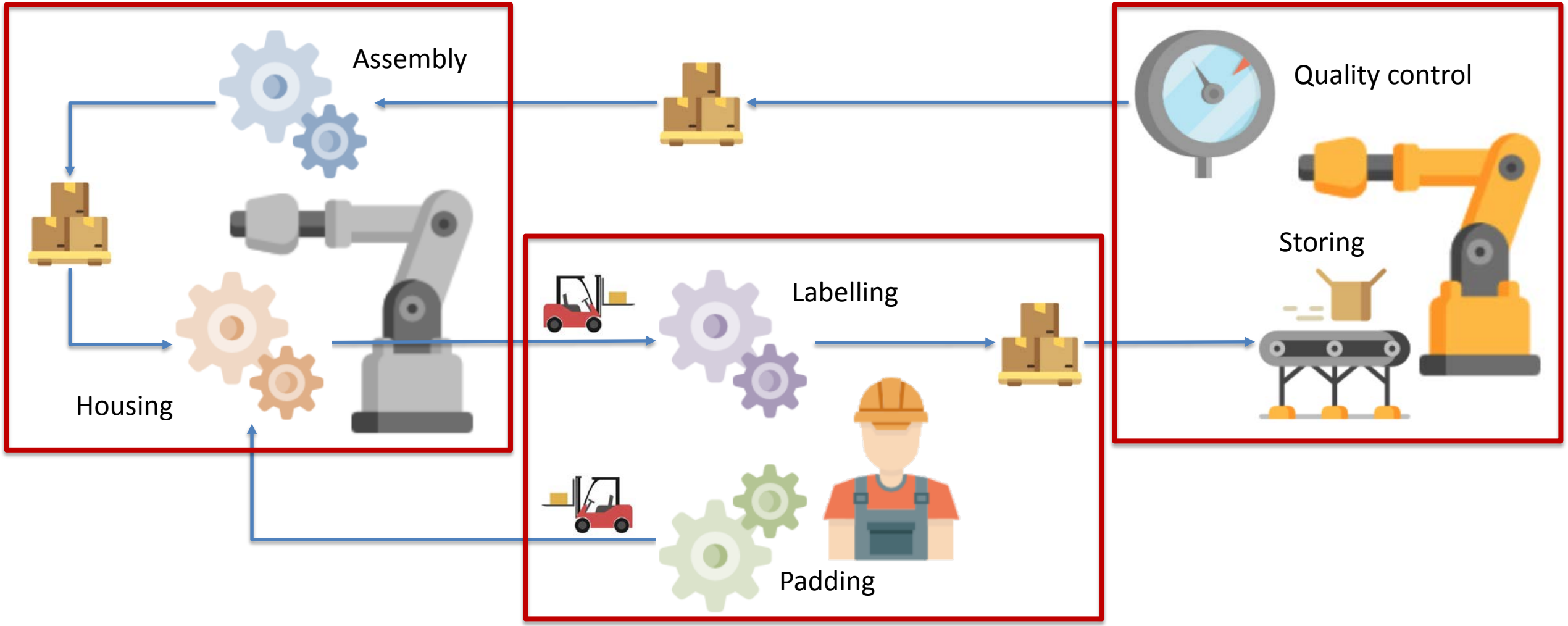


The experimental setup is composed by

- two robots
- human operator
- two linear axes

Each agent (human or robot) is responsible for two different operations.

Case study presentation



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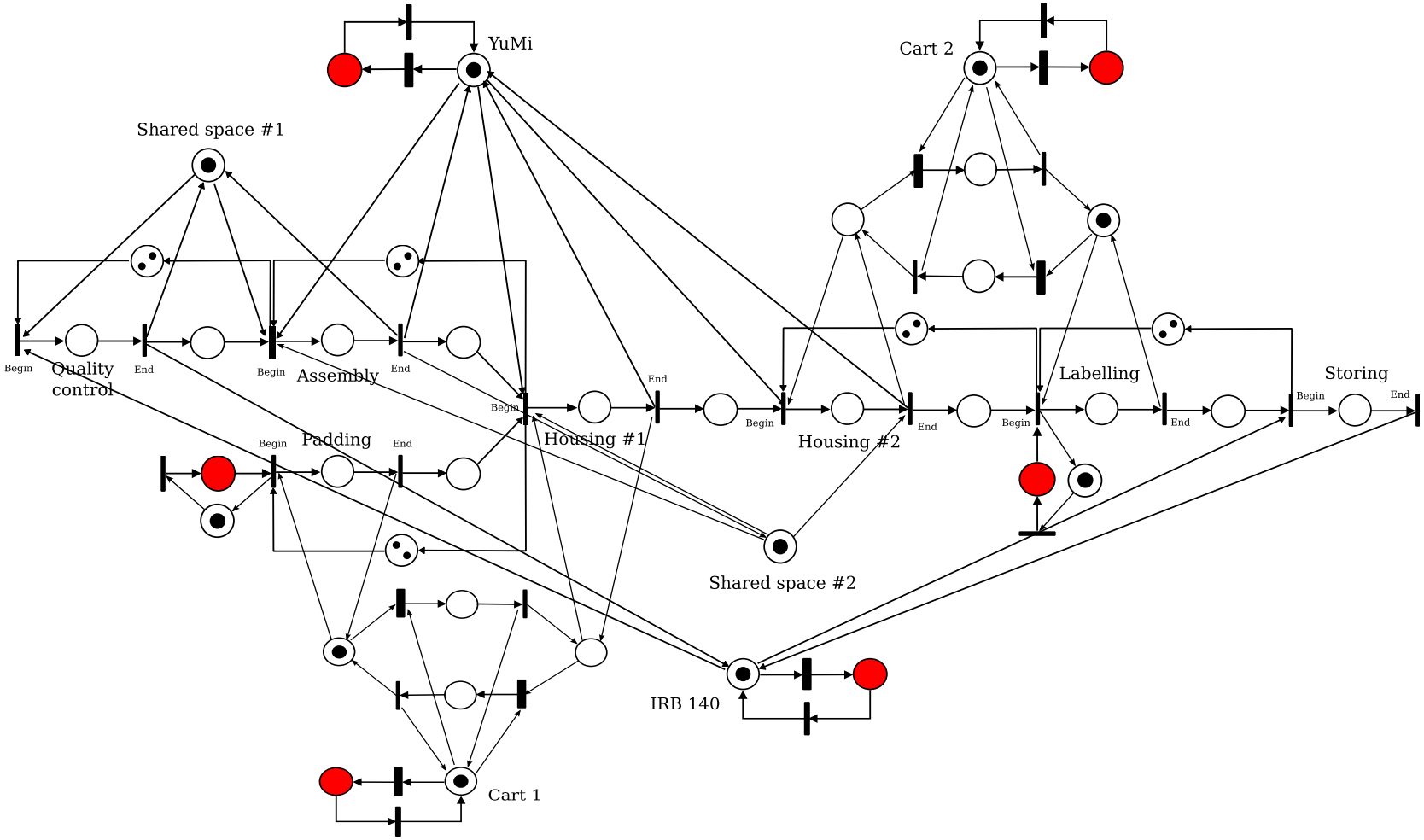
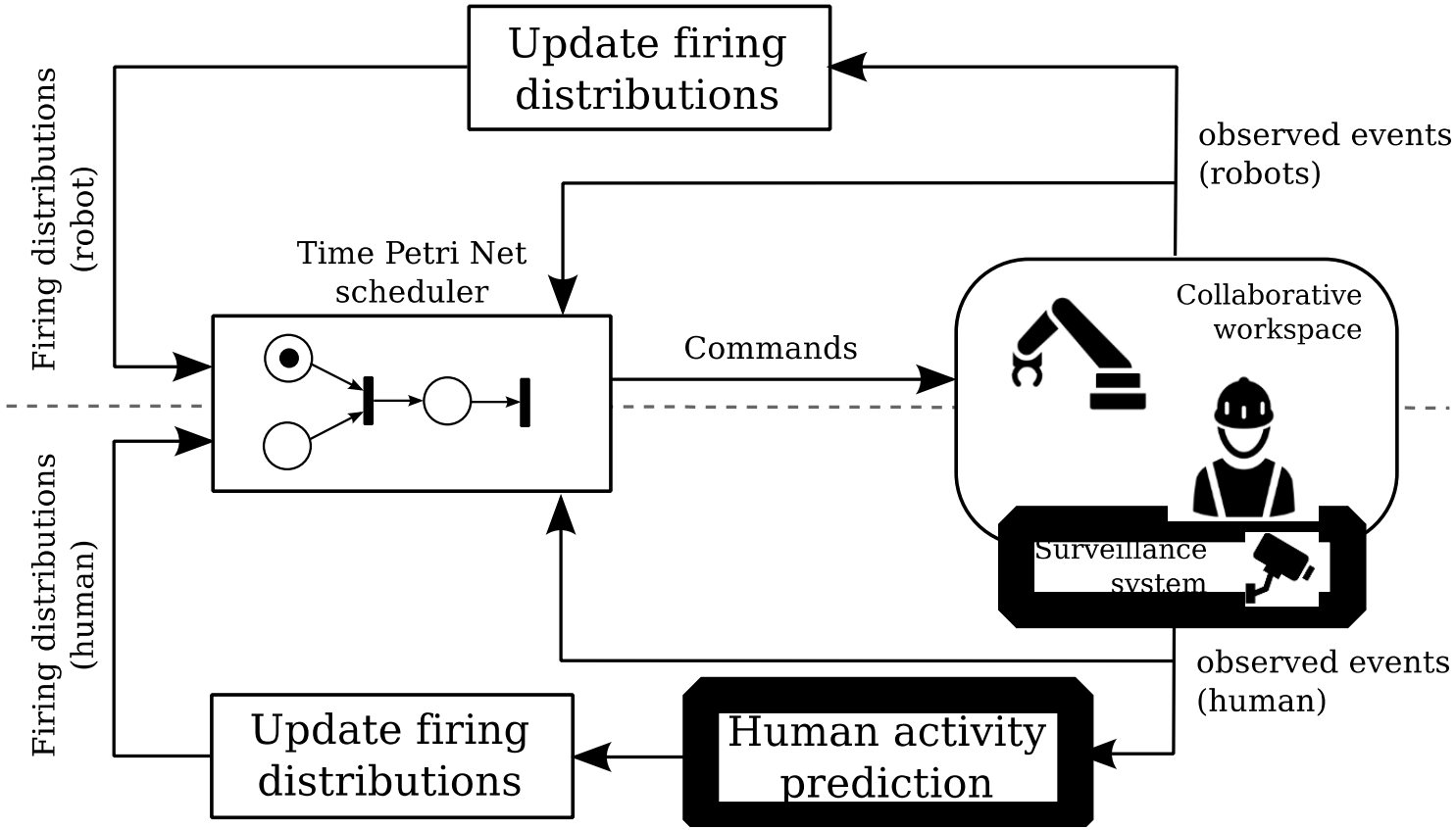
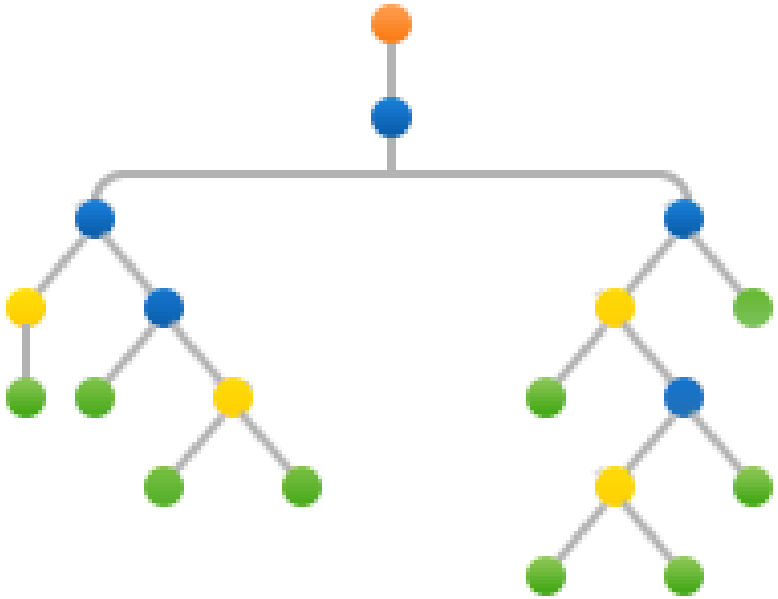
Modelling, control and experiments



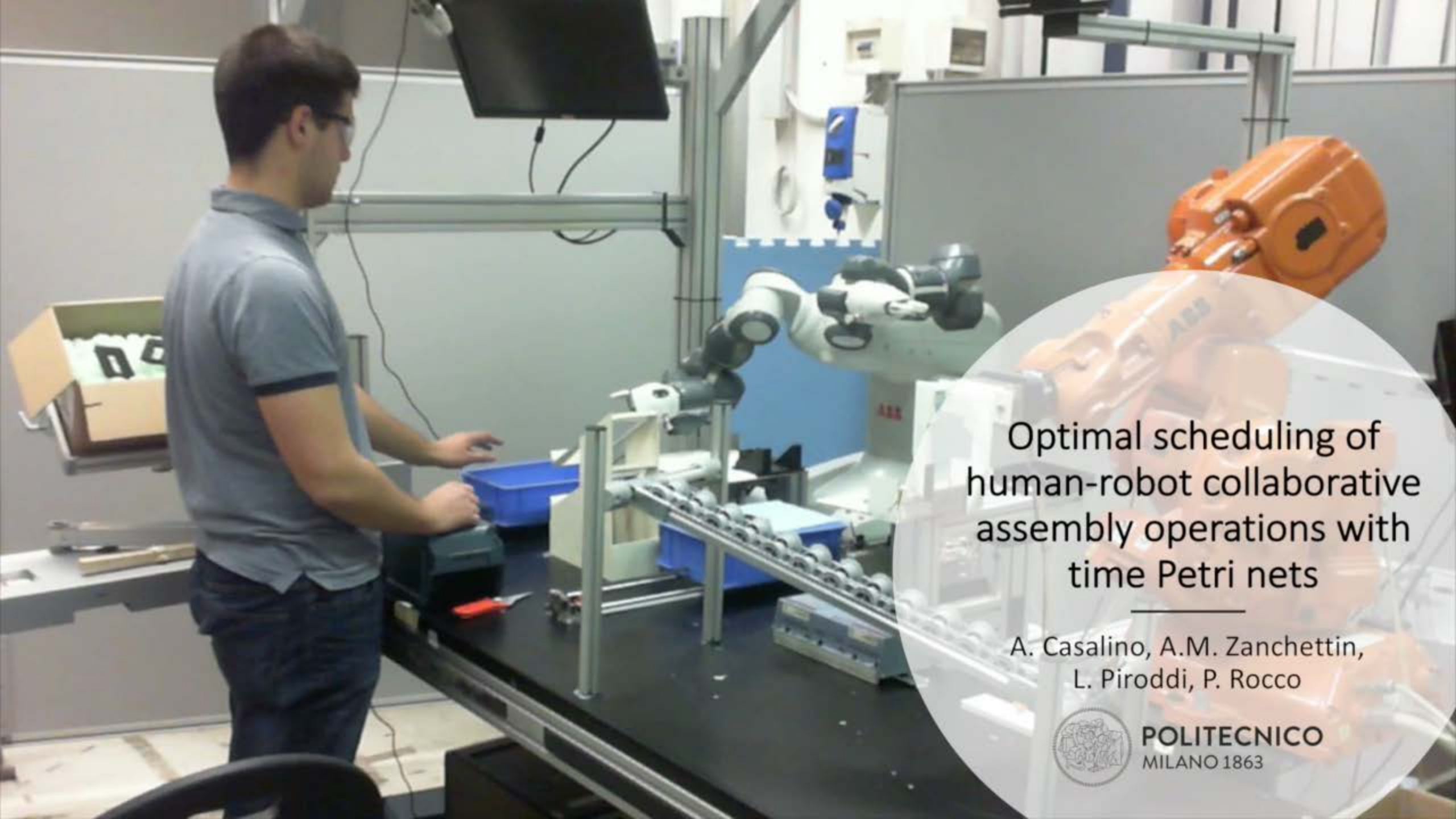
Modelling, control and experiments



Casalino, A., Zanchettin, A.M., Piroddi, L., Rocco, P. IEEE Tran ASE (under review)



A decision tree is used to simulate future execution of the discrete event system and to evaluate the best Policy (scheduling)



Optimal scheduling of human-robot collaborative assembly operations with time Petri nets

A. Casalino, A.M. Zanchettin,
L. Piroddi, P. Rocco

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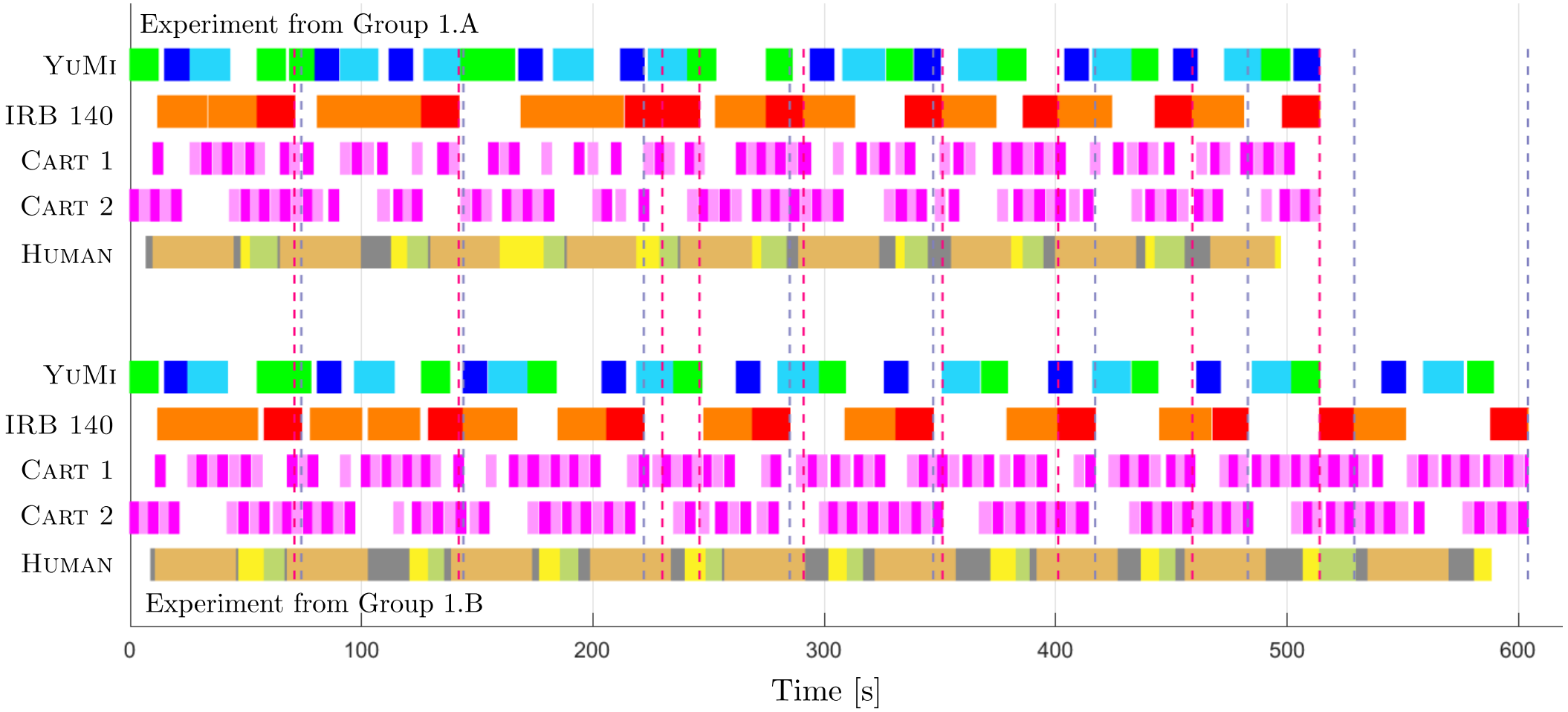
Modelling, control and experiments



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