

ABSTRACT**METHOD FOR GUIDING A ROBOT ARM, GUIDANCE SYSTEM**

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Method for guiding in real time a robot arm (6) for the processing of data of the surface of a body comprising the steps of:

- Generating a body model (MOD_P) comprising a meshing (M_1 , M_2) of points;
- 10 ▪ Planning a treatment trajectory (TRAJ₁) on the surface of the body model (MOD_S) by means of a calculator; parameters of sensors
- Activation of at least one transmission of a transmitter and/or acquisition of a sensor of an operator device (8), said operator device (8) being arranged at the distal end of the robotised arm
- 15 (6), the activation being carried out when the orientation of the axis of the sensor or the transmitter is merged with a predefined straight line passing through the target point (P_{TARGET}), said target point (P_{TARGET}) being referenced on the generated body
- 20 model (MOD_P).

Figure for the abstract: Fig.3