

Abstract

An interference preventing method for industrial robots comprising a step (II) of reading a present position of the hand, a step (III) of computing the difference between the taught target position and the present position of the hand, a step (IV) of judging whether this difference is within a predetermined range or not, a step (V) of setting a moving speed of the hand to a predetermined normal speed when the difference is within the predetermined range, a step (VI) of setting the moving speed of the hand to a predetermined low speed when the difference is out of the predetermined range, and a step (VII) of moving the hand automatically to the target position at the set speed. When the hand is moved over a long distance in the case of which interference is liable to occur, the moving speed thereof is low; when the hand is moved over a short distance, the moving speed thereof is normal.

Therefore, the hand can be stopped easily just before interference occurs, and the overall operation efficiency can be improved.