

Abstract

The invention relates to a method for learning and executing mutually coordinated paths (11, 22) of a first robot manipulator (10) and a second robot manipulator (20), comprising the steps: - manually guiding (S1) a first reference point of the first robot manipulator (10) over a desired first path (11), - acquiring (S2) the first path (11) or acquiring a first set of poses for the first path (11) and storing the first path (11) or the first set of poses in a first data set, - automatic traveling (S3) along the first path (11) according to the first data set, - during the automatic travel along the first path (11): manually guiding (S4) a second reference point of the second robot manipulator (20) over a desired second path (22), - acquiring (S5) the second path (22) or acquiring a second set of poses for the second path (22) and storing the second path (22) or the second set of poses in a second data set, wherein the second data set is assigned to the first data set so that a location of the first path (11) is at least approximately assigned to each location of the second path (22), and - synchronized traveling along the first path (11) by the first robot manipulator (10) according to the first data set and traveling along the second path (22) by the second robot manipulator (20) according to the second data set.

[Figure 1]

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