Claims

1. A robot having a robot manipulator (101) with an effector, wherein the robot manipulator (101) is designed and constructed for picking up, handling, and releasing an object and is controlled/regulated by a control unit (103), wherein the control unit (103) executes the following control program:
   - after the effector releases the object in accordance with a control program, the robot manipulator (101) executes a predefined movement, in which the effector is passed by a wiping object (104) in such a manner that any object still adhering to the effector is wiped off on the surface of the wiping object (104).

2. A robot having a robot manipulator (101) with an effector, wherein the robot manipulator (101) is designed and constructed for picking up, handling, and releasing an object and is controlled/regulated in accordance with a control program by a control unit (103), comprising a first sensor means (105), which is designed and constructed to determine persisting adherence of the object to the effector after a release of the object by the effector in accordance with a control program, and to generate a signal S in the presence of such persisting adherence, wherein the control unit (103) is designed and constructed to execute the following control program:
   - where a signal S is present, control the robot manipulator (101) in such a manner that it executes a predefined movement B, in which the effector is passed by a wiping object (104) in such a manner that the adhering object is wiped off on the surface of the wiping object (104).

3. The robot according to either of claims 1 or 2,
   in which a second sensor means (106) is available, with which collisions of the robot manipulator (101) with collision objects can be determined, wherein the second sensor means (106) executes the following control program: in the event such a collision is determined upon a movement of the robot manipulator (101) after a release of an object by the effector in accordance with a control program, a signal S1 is generated, wherein the control unit (103) is designed and constructed to execute the following control program:
   - where a signal S1 is present, control the robot manipulator (101) in such a manner that it executes a predefined movement B1, in which the effector is passed by a

wiping object (104) in such a manner that the adhering object is wiped off on the surface of the wiping object (104).

4. The robot according to any of claims 1 to 3,
in which the robot manipulator is force-controlled and/or impedance-controlled and/or admittance-controlled, and in which the control unit (103) executes the following control program:
   - if forces/moments acting on the robot manipulator (101) externally during the wipe-off on the wiping object (104) exceed predefined limits, the robot manipulator (101) is controlled such that it assumes a predefined state.

5. The robot according to any of claims 1 to 4,
in which the robot has a data interface to a data network, and the robot is designed and constructed to load control programs for the control unit from the data network.

6. The robot according to any of claims 1 to 5,
in which the robot is designed and constructed to load control and regulation parameters to the control programs from the data network.

7. The robot according to any of claims 5 to 6,
in which the robot is designed and constructed such that the loading of control programs and/or of corresponding control and regulation parameters from the data network is controlled by a remote station, which is likewise connected to the data network.

8. The robot according to any of claims 5 to 7,
in which the remote station and/or the manual input interface has a human-machine interface, which is designed and constructed for the input of control programs and/or corresponding control and regulation parameters, and/or for the selection of control programs and/or corresponding control and regulation parameters from a plurality of available control programs and/or corresponding control and regulation parameters.

9. A method for operating a robot, which has a robot manipulator (101) with an effector, wherein the robot manipulator (101) is designed and constructed for picking up, handling, and releasing an object and is controlled/regulated by a control unit (103),

10. wherein the control unit (103) executes a control program with the following steps:
    - after the effector releases the object in accordance with a control program, the robot manipulator (101) is controlled such that a predefined movement is executed, in which the effector with the object possibly still adhering is passed by a wiping object (104) in such a manner that the adhering object is wiped off on the surface of the wiping object (104).

11. A method for operating a robot, which has a robot manipulator (101) with an effector, wherein the robot manipulator (101) is designed and constructed for picking up, handling, and releasing an object and is controlled/regulated by a control unit (103), wherein the control unit (103) executes a control program with the following steps:
    - with a first sensor means, determination (201) of a persisting adherence of the object to the effector after release of the object by the effector in accordance with a control program;
    - generation (202) of a signal S in the presence of such persisting adherence of the object;
    - where a signal S is present, control (203) of the robot manipulator (101) in such a manner that it executes a predefined movement, in which the effector with the persistently adhering object is passed by a wiping object (104) in such a manner that the adhering object is wiped off on the surface of the wiping object (104).