

## **ABSTRACT**

A controller (3) is configured to operate a robot arm (10, 12) at a speed that is equal to or lower than a first maximum speed in a high-speed operation region (20H), and operate the robot arm (10, 12) at a speed that is equal to or lower than a second maximum speed lower than the first maximum speed in a low-speed operation region (20L), and change a collision detection sensitivity between the high-speed operation region (20H) and the low-speed operation region (20L) so that the collision detection sensitivity in the high-speed operation region (20H) becomes lower than the collision detection sensitivity in the low-speed operation region (20L).