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Gomi et al.

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(54) **ROBOT**

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See application file for complete search history.

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(57) **ABSTRACT**

A robot includes a base, first and second arms, first and second drive sources, first and second inertia sensors, and first and second angle sensors. A rotation axis of the first arm and a rotation axis of the second arm are orthogonal to each other. The first inertia sensor is installed at the first arm, and the second inertia sensor is installed at the second arm. The first angle sensor is installed at the first drive source, and the second angle sensor is installed at the second drive source. Angular velocities obtained from the first inertia sensor and the first angle sensor are fed back to a first drive source control unit. Angular velocities obtained from the second inertia sensor and the second angle sensor are fed back to a second drive source control unit.

7 Claims, 14 Drawing Sheets

