

# Design and Implementation of CORDIC-Based Joint Angle Processor for Robot Arm

莊英慎, 宋志雲

Electronics Engineering

Engineering

bobsung@chu.edu.tw

## Abstract

This paper presents a novel architecture of a joint angle processor for robot arm. The objective of the proposed CORDIC-based joint angle processor is to provide a hardware solution for computing the inverse kinematic for a robot arm control system. The complicated trigonometry operation is computed by the famous CORDIC algorithm. Simulation results show that the proposed joint angle processor achieves high precision. Moreover, an efficient pipelined architecture for VLSI and FPGA implementation is also proposed, this architecture has the advantage of saving hardware cost and power consumption. As a result, the proposed CORDIC-based joint angle processor provides a high speed inverse kinematic computation that assists the main MCU to operate the robot arm at real time.

Keyword : CORDIC, joint angle processor, inverse kinematic, FPGA, robot