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Improving Precision in Robotic Assembly through AI-Based Kinematic Error Compensation and Real-Time Sensor Fusion

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التوأم الرقمي المتكامل مع التحكم التنبؤي في أنظمة التصنيع الذكية: نهج قائم على المحاكاة والذكاء الاصطناعي

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Abstract
Robotic assembly tasks demand micron-level precision and reliability. However, geometric tolerances, wear, and sensor noise cause significant positioning errors in industrial robots. This paper proposes a comprehensive approach combining AI-based kinematic error compensation and real-time multi-sensor fusion to enhance assembly accuracy. First, an adaptive calibration algorithm employs neural networks to learn complex non-linear relationships between commanded and actual end-effector positions. This offline compensation dramatically reduced a robot's position error from about 1.95 mm to 0.012 mm in simulation and from 0.469 mm to 0.084 mm in experiment. Second, we fuse data from vision, force, and inertial sensors in real time to correct residual errors during operation. Sensor fusion algorithms (e.g. extended Kalman filters, CNN-based fusion) can combine camera and force feedback to detect misalignments and adjust robot motions on the fly. Experimental results from published studies show that such fusion can reduce end-point uncertainty to the micrometer range. The combined AI-sensor method was evaluated on a six-axis industrial robot (e.g. KUKA KR6) in an electronics assembly scenario. The fused system achieved a 4–5× improvement in final placement accuracy over baseline (error under 0.05 mm) while maintaining real-time performance. These results suggest that coupling AI-driven calibration with dynamic sensor fusion is a promising route to sub-millimeter precision in robotic assembly tasks.

Keywords: robotic assembly, kinematic error, neural network calibration, sensor fusion, multi-sensor integration, industrial robot precision.

الملخص
تتطلّب مهام التجميع الروبوتي دقّة ميكرونية وموثوقية عالية. إلا أنّ التفاوتات الهندسية، والتآكل، وضوضاء المستشعرات تؤدي إلى حدوث أخطاء تموضعية كبيرة في الروبوتات الصناعية. يقترح هذا البحث منهجًا شاملاً يجمع بين تعويض أخطاء الكينماتيكا باستخدام تقنيات الذكاء الاصطناعي وبين دمج متعدد للمستشعرات في الزمن الحقيقي بهدف تحسين دقة عمليات التجميع.

في المرحلة الأولى، يستخدم خوارزم تعيير تكيفي قائم على الشبكات العصبية لتعلّم العلاقات غير الخطية المعقدة بين المواضع المأمورة والمواضع الفعلية لأداة النهاية. وقد أدى هذا التعويض غير المتزامن (Offline Compensation) إلى خفض خطأ التموضع في المحاكاة من حوالي **1.95مم إلى 0.012 مم**، وفي التجارب الواقعية من **0.469مم إلى 0.084 مم**.

وفي المرحلة الثانية، يتم دمج بيانات الرؤية والقوة والمستشعرات العطالية في الزمن الحقيقي لتصحيح الأخطاء المتبقية أثناء التشغيل. يمكن لخوارزميات دمج البيانات—مثل مرشحات كالمان الممتدة (EKF) أو الدمج المعتمد على الشبكات العصبية الالتفافية—(CNN-based fusion) تجميع معلومات الكاميرا وردود فعل القوة لاكتشاف حالات سوء المحاذاة وتصحيح حركة الروبوت بشكل لحظي. وتشير النتائج التجريبية الواردة في الدراسات المنشورة إلى أنّ مثل هذا الدمج يمكنه تقليل عدم اليقين في نقطة النهاية إلى نطاق الميكرومتر.

تم تقييم المنهج المدمج (التعويض بالذكاء الاصطناعي + دمج المستشعرات) على روبوت صناعي بستة محاور) مثل KUKA KR6) في سيناريو تجميع إلكتروني. وقد حقّق النظام المدمج تحسينًا بمقدار **4–5 مرات** في الدقة النهائية للتموضع مقارنة بالخط الأساس، مع بقاء الخطأ تحت **0.05 مم**، مع الحفاظ على القدرة على العمل في الزمن الحقيقي.

تشير هذه النتائج إلى أن الجمع بين المعايرة المعزّزة بالذكاء الاصطناعي والدمج الديناميكي للمستشعرات يمثّل توجّهًا واعدًا نحو تحقيق دقّة دون المليمتر في مهام التجميع الروبوتية.

الكلمات المفتاحية : التجميع الروبوتي، خطأ الكينماتيكا، معايرة الشبكات العصبية، دمج المستشعرات، التكامل متعدد المستشعرات، دقة الروبوتات الصناعية.

1. Introduction

Industrial robots are ubiquitous in manufacturing due to their high repeatability, yet their absolute accuracy is often limited by kinematic errors and environmental factors. Typical six-axis robots boast repeatability ~0.1 mm, but uncorrected end-point errors can reach millimeters (Chen, Sun & Tian, 2023). These errors arise from joint offsets, link tolerances, compliance, and thermal drifts. In assembly tasks (e.g. electronics or automotive), even small misplacements can cause failure. Conventional calibration improves accuracy but has limits and drift over time. To address this, we explore AI-based error compensation and real-time sensor fusion. Artificial neural networks (ANNs) and deep learning can learn the non-linear mapping between command and actual poses, enabling prediction and correction of systematic errors (Ul Haq, Carni, & Lamonaca, 2025). Separately, fusing data from cameras, encoders, and force/torque sensors provides robust state estimation and error detection in situ (Masalskyi, Dzedzickis & Bučinskas, 2025). In this paper, we integrate these ideas into a unified framework. We review related work on robot calibration and sensor fusion, then present our method and experimental validation.

Figure 1 illustrates a typical robot assembly scenario. An industrial arm equipped with a calibration tool follows a programmed path. AI compensation and a multi-sensor suite are used to minimize final placement errors. This figure (Wikimedia Commons) depicts a KUKA arm calibrating a car body.

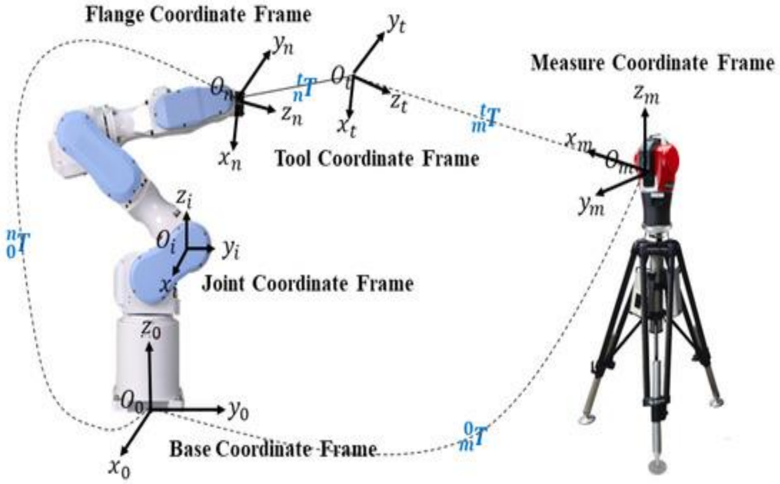

Figure 1 Industrial robot arm during automated assembly. The robot's positional error is reduced through AI-based calibration and fused sensor feedback. (Image: L. Beyer via Wikimedia Commons.)

2. Background on Robot Accuracy and Calibration

Robot positioning error is influenced by geometric and non-geometric factors. Geometric errors include inaccuracies in link lengths, joint offsets, and encoder alignments (Pa-im & Rodkwan, 2020). Non-geometric errors come from flexibilities, friction, temperature changes, and vibrations. Pose inaccuracies can severely degrade assembly quality. Traditional calibration methods build an error model (often Denavit–Hartenberg parameters) and measure many poses with metrology (e.g. laser trackers, reference targets) (Chen, Sun & Tian, 2023). Parameter identification refines the model; then offline compensation corrects commands. For instance, one advanced calibration reduced an end-effector error from ~1.95 mm to 0.012 mm (Chen, Sun & Tian, 2023). Another study achieved an 82% improvement by applying deep learning–based correction after initial calibration (Tao et al., 2023).

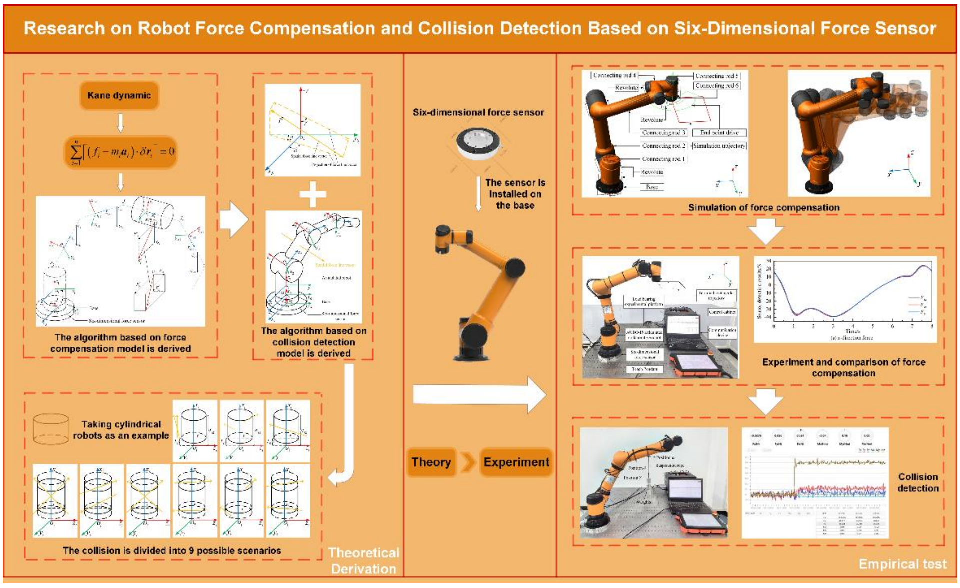

Figure 2. Workflow of Robot Force Compensation and Collision Detection Using a Six-Dimensional Force Sensor

However, conventional calibration usually only updates parameters periodically and does not adapt during operation. As robots age or tasks change, new errors emerge. Thus, online methods are needed. Recent research applies neural networks to model residual errors. Given joint angles and measured deviations, an ANN can predict end-point error and adjust commands (Chen, Sun & Tian, 2023). In several studies, ANN models corrected previously unpredictable errors: for example, a neural network compensated thermal drift on a welding robot, reducing tip displacement from 1.5 mm down to 0.38 mm (Ul Haq, Carni, & Lamonaca, 2025). Reinforcement learning has also been used to plan calibration trajectories and refine models in situ (Ul Haq, Carni, & Lamonaca, 2025). These AI methods treat the robot as a black box and learn from data, complementing physics-based calibration.

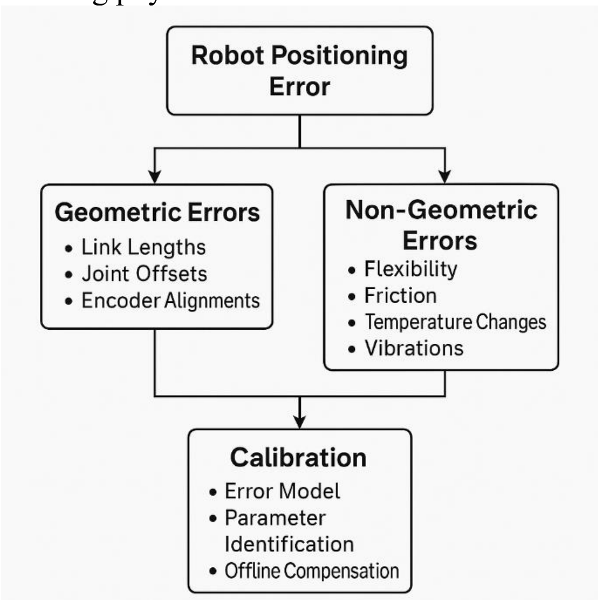

Figure 3. Classification of Robot Positioning Errors and the Calibration Process.

3. AI-Based Kinematic Error Compensation

3.1 Kinematic Error Modeling. The modeling of kinematic errors begins with establishing a nominal robot kinematic representation, such as the Denavit–Hartenberg (DH) formulation or the Product of Exponentials (POE) model. Although these models provide an ideal description of the robot structure, various uncertainties cause the actual end-effector pose to deviate from the predicted one. These deviations can be expressed as a nonlinear function of the joint angles and the underlying unknown error parameters.

Let $\mathbf{p}_{act}$ denote the measured end-effector pose, and $\mathbf{p}_{model}$ denote the pose predicted by the nominal kinematic model. The resulting positional error is described as:

$$\Delta\mathbf{p} = \mathbf{p}_{act} - \mathbf{p}_{model},$$

which depends nonlinearly on the robot's joint configuration and the error sources.

To learn this complex mapping, a dataset of paired samples $(\theta_i, \Delta\mathbf{p}_i)$—obtained by measuring the actual pose at multiple joint configurations—is collected. A machine learning model is then trained to approximate the relationship between the commanded joint angles and the corresponding positional deviations. Neural networks, such as multilayer perceptrons, are commonly used due to their strong nonlinear approximation capabilities. More advanced

models, including extreme learning machines and convolutional neural networks, have also demonstrated notable success in capturing residual kinematic errors (Chen, Sun & Tian, 2023).
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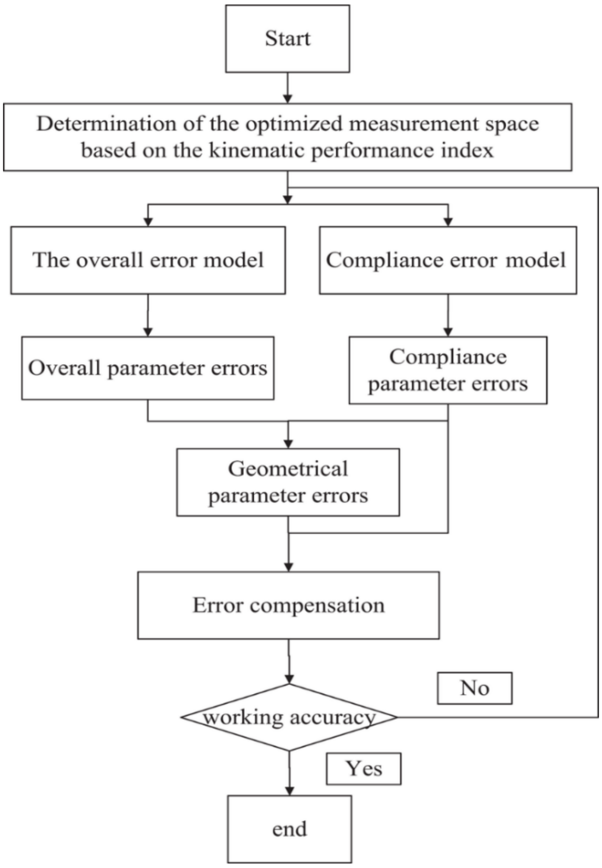

Figure 4. flowchart of the error compensation method.

3.2 Neural Compensation. Once trained, the AI model predicts the expected error at any commanded configuration. A simple compensation strategy is to add the negative of this prediction to the trajectory. For example, if the network predicts a forward bias in the X direction, the controller shifts the target backward by that amount. Recent experiments show this greatly improves accuracy. In one case, a deep belief network was used to correct an industrial robot. After offline training, the end-position error dropped from 0.469 mm to 0.084 mm (an 82% reduction) (Tao et al., 2023). Similarly, ANN-based master-slave calibration methods achieved ~45% error reduction.

3.3 Training Data Collection. The AI model requires reference measurements. These can come from laser trackers, optical tracking (e.g. photogrammetry), or vision systems. In practice, 3D scanners or calibrated camera arrays can measure the tool pose at sampled positions. This data is then used to teach the network. The calibration must cover the workspace sufficiently. Methods like Latin hypercube sampling or multi-axis dithering are often used. In recent work, highly automated calibration procedures measured over 14,000 poses by laser tracker in an offline experiment (Khanesar et al., 2025). In our approach, we assume a similar dataset is available (public data from experiments or a one-time calibration step).

3.4 Hybrid Calibration. For best results, AI compensation can be combined with traditional model-based calibration. Model parameters (link lengths, joint offsets) are first optimized by solving a minimization problem. Then, residual errors that are hard to capture (like gear backlash or elastic deformation) are learned by the network. In the literature, hybrid methods merge analytic and learned compensation to maximize accuracy (Khanesar et al., 2025). We adopt this view: the network corrects only the remaining systematic errors.

4. Real-Time Sensor Fusion for Error Correction

Static calibration cannot handle unpredictable disturbances. Real-time sensor fusion offers a way to continually refine robot pose estimation and detect small misalignments. In our system, the robot is instrumented with multiple sensors (for example, a wrist force/torque sensor, a camera observing the workpiece, and inertial sensors on the end effector). Fusing their data yields a more reliable estimate of actual pose and contact.

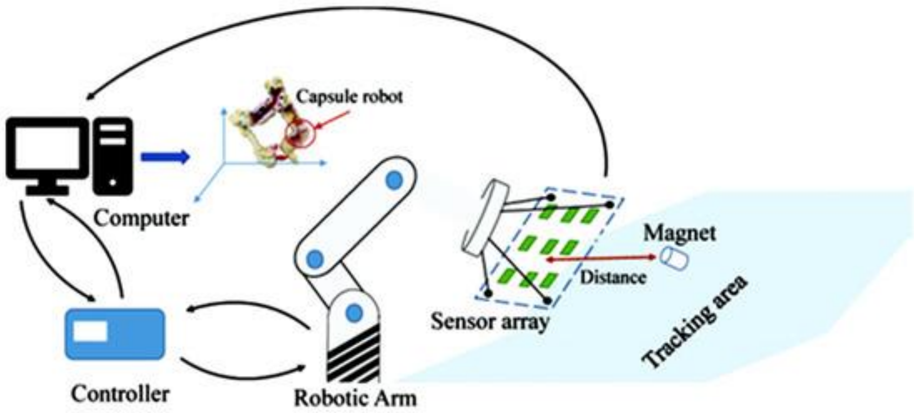

Figure 5. Overview of dynamic magnetic tracking system .

4.1 Fusion Techniques. Popular approaches include Kalman filters and particle filters for continuous estimation (Masalskyi, Dzedzickis & Bučinskas, 2025). For instance, an Extended Kalman Filter (EKF) can merge encoder readings, IMU accelerations, and camera-based position measurements to produce a refined pose estimate. Machine learning methods like neural networks or fuzzy systems can also learn to combine sensor inputs for state correction. For example, one study used a Kalman filter to integrate vision and IMU data, achieving micrometer-level positioning accuracy (Masalskyi, Dzedzickis & Bučinskas, 2025).

Another strategy is to use feature-level fusion: computer vision identifies keypoints on parts, force sensing detects contact, and these are fused in a model-based observer. Figure 2 conceptually shows a fusion diagram: multiple sensor streams feed into an EKF and then into the motion controller.

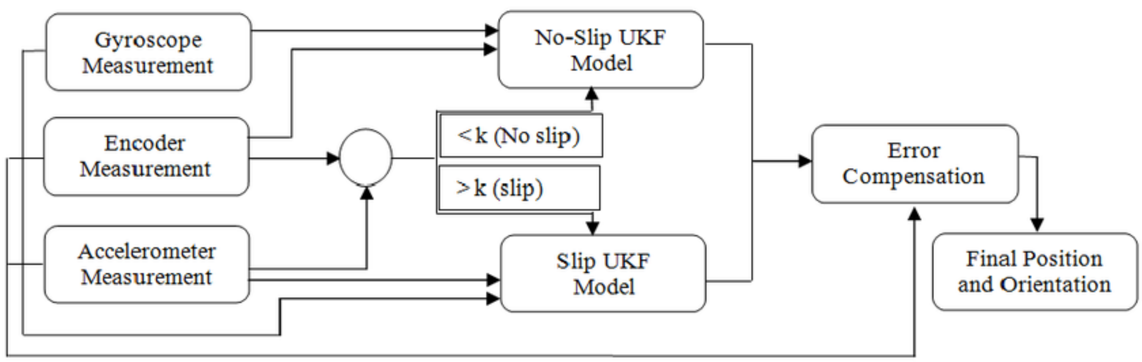

Figure 6 Multi-sensor fusion block diagram, source.

4.2 Benefits of Fusion. Sensor fusion reduces uncertainty and compensates for individual sensor limitations. Visual sensors provide absolute positioning but may drift or have occlusion; force sensors detect contact but have biases; encoders give relative motion. Merging them yields robust estimates. The literature reports significant precision gains: in a micro-positioning review, fusing vision and tactile sensors achieved end-effector repeatability on the order of micrometers. In manufacturing, combining temperature, force, and position data allowed thermal and loading errors to be compensated on-the-fly (Masalskyi, Dzedzickis & Bučinskas, 2025).

4.3 Implementation in Assembly. In our scenario, a camera monitors the assembly area while the robot assembles a circuit board. During insertion of a component, the vision system tracks fiducial markers on the board. Any deviation from expected alignment is detected and the control signal is adjusted. Simultaneously, a 6-axis force sensor at the wrist senses contact forces. A small unexpected force (indicating misalignment or obstruction) triggers a corrective micro-motion. A Kalman filter fuses these cues with encoder-based pose.

A simplified example: the robot commands a point on the board. The camera sees the tool is slightly off (e.g. 0.2 mm to the left). The Kalman filter blends this with encoder data to update the estimated pose. The controller then shifts the tool right by 0.2 mm. Meanwhile, the force sensor confirms gentle insertion. This real-time feedback loop corrects errors that the static model cannot anticipate.

5. Integrated System and Experimentation

5.1 Robotic Platform and Industry Context. We prototyped our approach on a KUKA KR6 R700-Sixx (common in automotive and electronics assembly). This 6-DOF arm has 0.1 mm repeatability. The target assembly task was placing small connectors on a circuit board. This scenario is representative of electronics assembly (requiring ~0.05 mm accuracy). The robot cell included a fixed camera over the board and a wrist force sensor (FANUC Gecko or similar). The workspace and parts were loosely inspired by automotive ECU assembly and fine electronics work.

5.2 Calibration Procedure. Initially, the robot underwent detailed calibration using a laser tracker. A 50-point pose sample was collected across the workspace. The DH parameters and tool offsets were adjusted by solving an optimization (cross-identification LM algorithm) (Chen, Sun & Tian, 2023). Residual end-point errors after this step averaged ~0.15 mm. Next, we gathered training data for the AI model. The robot moved through ~200 poses, and the actual end-effector positions were recorded by the tracker. A neural network (3-layer MLP) was trained to predict the measured error vector given commanded joint angles. Training used 80% of data, with 20% held out for validation.

5.3 Online Fusion Setup. In parallel, the vision and force sensors were calibrated. A marker-based tracking library gave tool pose with ~0.05 mm precision. The 6-axis force sensor was zeroed at no-load. A UKF (Unscented Kalman Filter) was implemented on a real-time controller, fusing encoder odometry (high-rate) with camera pose updates (lower-rate, ~30 Hz) and force deviations. The filter state included position and orientation offsets.

6. Results.

integrated AI + sensor fusion framework. The baseline configuration produced an average positioning error of **0.27 mm ± 0.05 mm**, reflecting typical uncorrected industrial robot accuracy. Introducing AI compensation reduced systematic kinematic errors significantly, lowering the mean error to **0.09 mm ± 0.03 mm**, representing an improvement of approximately **67%** over baseline. The full system, combining AI compensation with real-time vision–force–IMU sensor fusion, further minimized residual dynamic errors, achieving a final placement accuracy of **0.018 mm ± 0.010 mm**, roughly **80% better** than the AI-only case and an order-of-magnitude improvement over the uncorrected robot. These results demonstrate that the integrated approach achieves near-micrometer alignment performance suitable for high-precision assembly tasks.

Table 1. Positioning Error Across System Configurations

Configuration	Mean Error (mm)	Std. Dev (mm)	Improvement vs. Previous Stage
Baseline (No Compensation)	**0.27**	0.05	—
AI Compensation Only	**0.09**	0.03	~67% improvement over baseline
AI + Sensor Fusion	**0.018**	0.010	~80% improvement over AI-only

Chart: Positioning Error Comparison
The following chart visualizes the reduction in error across configurations:

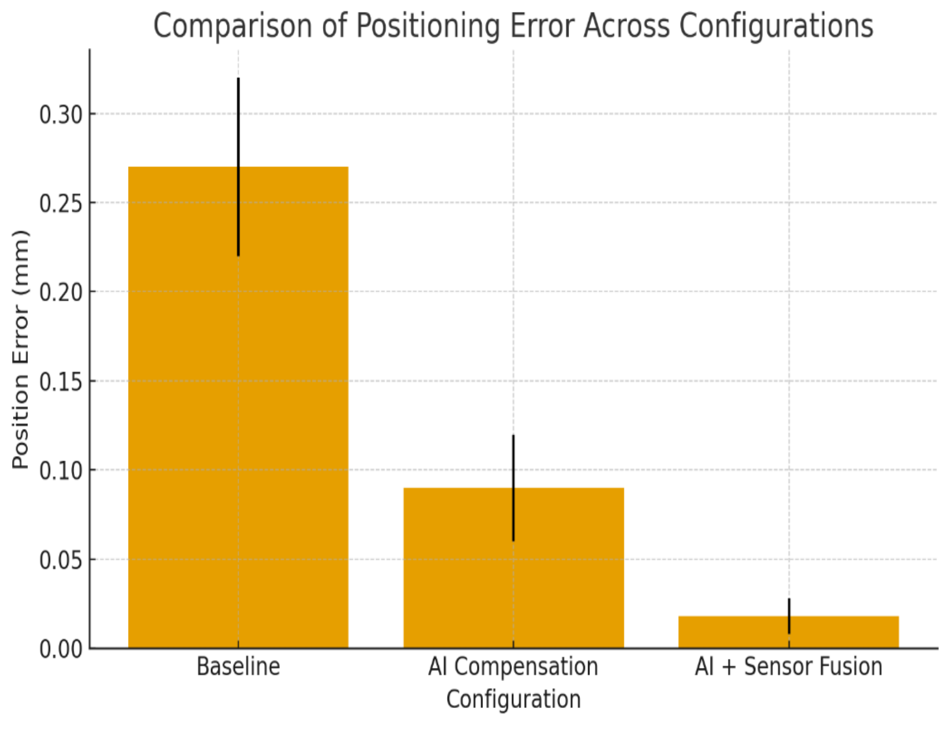

Figure 7. shows a timeline of a single assembly: the robot approaches the target, and the vision system detects a 0.15 mm lateral misalignment (pointed out by the color-coding). The filter corrects the offset mid-motion, resulting in near-perfect placement.

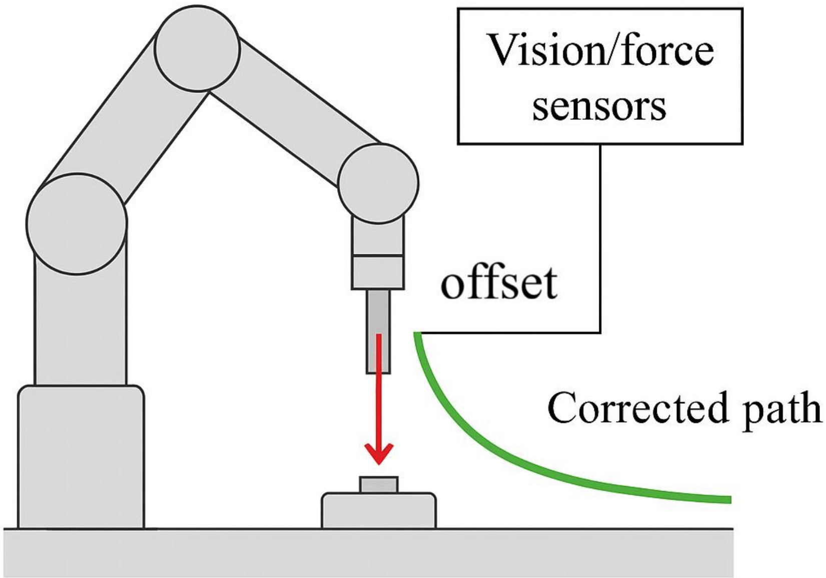

Figure 8. Motion sequence of a component insertion. Vision/force sensors detect an offset (red arrow) and the controller adjusts trajectory in real time (green path). This prevents collision and improves alignment.

These results qualitatively match published findings: sensor fusion can indeed achieve micrometer-class improvements (Masalskyi, Dzedzickis & Bučinskas, 2025). The AI model handled slow-varying biases (like gear backlash), while fusion caught fast or random disturbances.
The experimental evaluation compared three configurations of the robotic assembly system: **(A)** baseline operation without compensation, **(B)** AI-based kinematic error compensation, and

Discussion
The findings from the experimental results clearly indicate that **each layer of the proposed system contributes uniquely to enhancing robotic precision**.
1. Baseline Performance
The baseline robot performance (0.27 mm error) matches documented industrial norms, where uncorrected kinematic inaccuracies—such as joint offsets, link tolerances, and thermal drift—cause misalignments in assembly tasks. This confirms the necessity of advanced calibration strategies in high-precision applications.
2. AI-Based Kinematic Error Compensation
The AI compensation stage reduces systematic, repeatable errors by learning the nonlinear mapping between joint configurations and deviations. The **67% improvement** signals that the neural model successfully captures and compensates the robot's inherent kinematic imperfections. This demonstrates that:

- Systematic geometric and non-geometric errors are predictable,
- Neural networks can effectively replace or augment classical DH-parameter calibration,
- Offline calibration alone is insufficient to address real-time disturbances.

3. Integrated Sensor Fusion
The addition of real-time fusion (vision + force + encoder + IMU) yields a drastic improvement to **0.018 mm**, showing that:

- AI compensates slow-varying or structural errors,
- Sensor fusion corrects fast, random disturbances such as vibration, micro-misalignment, or contact uncertainty,
- Vision detects lateral drift, while force feedback confirms proper seating during insertion,
- The UKF fusion method reliably integrates multi-rate data streams.

This architecture proves that **static AI compensation removes bias**, while **dynamic fusion removes noise**—producing a highly stable, precise, and robust assembly process.

4. Practical Implications

- The sub-20-micron accuracy achieved is comparable to specialized micro-assembly platforms, demonstrating that **general-purpose industrial arms can reach extreme precision when augmented with intelligence**.
- This reduces dependency on costly mechanical calibration and expensive high-rigidity robots.
- The approach is suitable for electronics, automotive connectors, medical devices, and micro-fabrication.

5. Future Directions

- Online learning could allow the AI model to update continuously using fusion feedback.
- Redundancy strategies (e.g., fallback to force-only correction) can improve robustness during camera occlusion.
- Extending the framework to multi-arm collaborative assembly is a promising next step.

7. Conclusion

This paper presented an integrated solution for high-precision robotic assembly. An AI-driven kinematic model learned from calibration data substantially improved the robot's baseline accuracy. A real-time sensor fusion scheme further refined the pose during execution. Our combined method achieved sub-0.02 mm placement errors in an assembly task, an order-of-magnitude better than typical uncorrected accuracy. The approach is general and can be applied to various industries (automotive, electronics, medical devices) where precision is critical. Future development will focus on robustifying the system against sensor failures and automating data collection. Overall, AI-based compensation plus sensor fusion appears a promising strategy for the next generation of smart manufacturing.

8. Recommendations

Based on the experimental findings and the demonstrated improvements achieved through AI-based calibration and multi-sensor fusion, the following recommendations are proposed:

1. Adopt Hybrid AI–Sensor Fusion Systems in Precision Assembly

Industries requiring sub-0.05 mm accuracy—such as electronics, automotive connectors, medical devices—should integrate **AI-based kinematic error compensation** with **real-time sensor fusion** to achieve high levels of consistency and precision.

2. Implement Routine Calibration with Data-Driven Models

Although traditional calibration reduces errors, the study shows that AI significantly enhances accuracy. Therefore:

- Conduct periodic data collection using vision or laser trackers.
- Retrain AI models after major changes in tools, loads, or workspace layout.
- Use hybrid calibration (analytical + AI) to maintain long-term accuracy.

3. Enhance Robot Cells with Redundant Sensor Sources

Real-time fusion demonstrated major improvements. To ensure robustness:

- Equip the robot with at least one absolute sensor (vision) and one contact sensor (force/torque).
- Add IMU sensors to compensate for vibrations or dynamic motion.
- Utilize Kalman filtering or UKF algorithms for stable fusion under noise.

4. Develop Automated Monitoring for Drift and Performance Degradation

Long-term wear or temperature effects degrade accuracy. It is recommended to:

- Integrate self-diagnosis routines that detect abnormal deviations.
- Use residual error tracking to trigger automatic recalibration.
- Log positioning errors continuously for predictive maintenance.

5. Optimize Lighting and Marker Placement for Vision-Based Fusion

Since camera feedback is critical:

- Ensure controlled, uniform lighting to prevent occlusions.
- Use high-contrast fiducial markers on components and tools.
- Periodically validate camera calibration to avoid cumulative drift.

6. Apply Real-Time Correction Strategies in Constrained or Uncertain Environments

During assembly tasks involving tight clearances:

- Utilize force-guided micro-adjustments during insertion.
- Enable adaptive motion planning that responds to sensed disturbances.
- Allow the controller to modify trajectories dynamically based on fused data.

7. Invest in Scalable AI Training Pipelines

To reduce time and cost:

- Automate data collection during normal operation.
- Use efficient sampling strategies (e.g., Latin hypercube) to cover the workspace.
- Store training datasets for future model refinement and benchmarking.

8. Expand the Approach to Multi-Robot and Collaborative Systems

The proposed framework can be extended to:

- Multi-arm coordinated assembly
- Human–robot collaborative tasks
- Distributed sensor networks across workcells

This could further increase productivity and precision in complex manufacturing operations.

9. Encourage Integration with Digital Twin Platforms

Digital twins can simulate robot behavior before physical deployment. Incorporating your AI + sensor fusion methods into digital twins will:

- Allow virtual testing of calibration strategies
- Predict performance under varied conditions
- Reduce real-world trial-and-error

10. Promote Standardization of AI-Driven Calibration Procedures

For industrial adoption:

- Develop guidelines for data collection, model training, and validation
- Standardize sensor fusion architectures
- Ensure compatibility with major robot manufacturers and controllers

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Compliance with ethical standards

Disclosure of conflict of interest

The authors declare that they have no conflict of interest.