

A method of adaptation of an intelligent robot to the mass of working objects comprises displacement of a gripper by two gripping jaws. After that the jaws are gripped and information is recorded, and then vertical lifting of the gripper is performed. In the case, the information about slippage of the object is recorded. At the absence of information the processes of vertical lifting of gripper and increasing of compressive force are stopped. The identified value of a scalable compressive force is saved. Then the process of final gripping of the jaws is carried out with creation of the desired fixed value of compressive force. At the same time, for identification of the value of compressive force the process of increasing the compressive force is carried out continuously and simultaneously with continuous process of lifting gripper.