Contents

1 Introduction ... 1
References ... 6

2 State of the Art ... 7
2.1 Social and Cognitive Human-Robot Interaction ... 8
2.1.1 Multimodal Communication ... 9
2.1.2 Expressive Emotion-Based Interaction ... 9
2.1.3 Social-Cognitive Skills ... 9
2.2 Physical Human-Robot Interaction ... 9
2.2.1 Control ... 10
2.2.2 Human-Friendly Mechanical Design ... 11
2.2.3 Motion Planning and Obstacle Avoidance ... 13
2.2.4 Quantifying Human Safety ... 16
2.3 Robot Safety in Industrial Robotics ... 18
References ... 19

3 Soft-Robotics Control ... 25
3.1 Robot Dynamics and Modeling ... 26
3.1.1 Rigid Joint Model ... 26
3.1.2 Flexible Joint Model ... 29
3.2 Unified Control for the LWR-III ... 30
3.2.1 The DLR Lightweight Robot III ... 30
3.2.2 Control Architecture ... 31
3.2.3 Implementation in Joint Space ... 32
3.2.4 Implementation in Cartesian Space ... 34
3.3 Collision Detection Schemes ... 35
3.3.1 Energy-Based Detection ... 36
3.3.2 Direct Derivation Method ... 37
3.3.3 Derivation from Desired Dynamics ... 37
3.3.4 Observing Joint Velocity ... 38
3.3.5 Observing Generalized Momentum ... 39

3.3.6 Response Behavior of Momentum Observer 42
3.3.7 Comparison of Collision Detection Schemes 42
3.3.8 Practical Remarks 44
3.3.9 Estimating the Contact Wrench 46
3.4 Collision Reaction 47
3.4.1 Reflex like Collision Reaction Schemes 47
3.4.2 Trajectory Scaling 50
3.5 Experiments 56
3.5.1 Energy-Based Collision Detection 56
3.5.2 Balloon Test 57
3.5.3 Human Arm Measurements and Collision Test-Bed 59
3.5.4 Performance Comparison of Reaction Strategies 60
3.5.5 Collisions with the Human Arm and Chest 62
3.5.6 Trajectory Scaling 64
3.6 Summary 65
References 66

4 Biomechanics and Forensics 69
4.1 Classifying Injury Severity 69
4.1.1 The Abbreviated Injury Scale 70
4.1.2 EuroNCAP 71
4.2 Injury Criteria for the Head 71
4.2.1 Possible Head Injuries and Their Mechanisms 71
4.2.2 The Wayne State Tolerance Curve 73
4.2.3 Rotational Head Acceleration Limits 73
4.2.4 Head Injury Criterion 74
4.2.5 3 ms-Criterion 75
4.2.6 Converting Severity Indices to the Abbreviated Injury Scale 75
4.2.7 GAMBIT 76
4.2.8 Vienna Institute Index 77
4.2.9 Effective Displacement Index 78
4.2.10 Revised Brain Model 78
4.2.11 Maximum Mean Strain Criterion 78
4.2.12 Maximum Power Index 79
4.2.13 The Facial Laceration Criterion 80
4.2.14 Fracture Forces 80
4.3 Injury Criteria for the Neck 82
4.4 Injury Criteria for the Chest 83
4.4.1 Lobdell's Chest Model 83
4.4.2 Force Criterion 84
4.4.3 Acceleration Criterion 84
4.4.4 Compression Criterion 85
4.4.5 Viscous Criterion 86
4.5 Eye Injury 86

References ... 86

5 Crash-Testing in Robotics ... 91
5.1 Automobile Crash Testing ... 93
5.2 Blunt Unconstrained Impacts with the LWR-III ... 95
5.2.1 Experimental Setup ... 95
5.2.2 Results for the Head ... 96
5.2.3 Results for the Neck ... 98
5.2.4 Results for the Chest ... 101
5.2.5 Parenthetic Evaluation and Discussion ... 101
5.2.6 Human-Robot Impacts ... 105
5.2.7 Influence of Robot Mass and Velocity ... 107
5.3 Blunt Unconstrained Impacts for General Robots ... 109
5.3.1 Evaluated Robots ... 110
5.3.2 Head Injury Criterion and Impact Forces ... 110
5.4 Constrained Blunt Impacts ... 114
5.4.1 Types of Blunt Clamping ... 115
5.4.2 Braking Tests ... 116
5.4.3 Experimental Results with the LWR-III and KR6 ... 118
5.4.4 Simulations ... 120
5.5 Constrained Contact with Singularity Forces ... 124
5.6 Towards a Crash-Testing Protocol ... 128
5.6.1 Experimental Setup ... 129
5.6.2 The DLR Crash Report ... 129
5.6.3 Case Discussions ... 135
5.7 Summary ... 143
References ... 144

6 Sharp and Acute Contact ... 149
6.1 Soft-Tissue Injury Caused by Sharp Tools ... 151
6.1.1 Biomechanics of Soft-Tissue Injury ... 152
6.1.2 The Depth of Vital Organs ... 153
6.1.3 Braking Distance ... 155
6.1.4 A Simulation Use-Case with the LWR-III ... 156
6.2 Experiments ... 159
6.2.1 Investigated Tools ... 159
6.2.2 Silicone Block ... 159
6.2.3 Pig Experiments ... 160
6.2.4 Human Experiments ... 168
6.3 Summary ... 169
References ... 170

7 Reactive Pre-collision Strategies ... 171
7.1 Reaction Strategy with Task Preservation ... 172
7.1.1 Proximity Disturbance Signals ... 173
7.1.2 Experiment ... 174
7.2 Reaction Strategy without Task Preservation ... 175
7.2.1 Algorithm Design ... 176
7.2.2 Implementation ... 182
7.2.3 Simulations ... 186
7.2.4 Experiments ... 188
7.3 Summary ... 193
References ... 193

8 Towards the Robotic Co-worker ... 195
8.1 Functional Modes ... 197
8.2 Interaction Concept ... 199
8.2.1 Proximity and Task Partition ... 200
8.2.2 Interaction Layer ... 200
8.2.3 Absolute Task Preserving Reaction ... 201
8.2.4 Task Relaxing Reaction ... 203
8.2.5 Dealing with Physical Collisions ... 203
8.2.6 Safety Architecture ... 203
8.3 Interactive Bin Picking ... 206
8.3.1 Vision Concept ... 207
8.3.2 Soft-Robotics Control for Grasping ... 210
8.3.3 Autonomous Task Execution ... 210
8.3.4 Evaluation of Grasping Success ... 211
8.3.5 Extension to Interactive Bin-Picking ... 212
8.4 Summary ... 214
References ... 214

9 Competitive Robotics ... 217
9.1 Preliminaries ... 219
9.2 Safety of the Human ... 221
9.2.1 Physical Interaction in Humanoid Robot Soccer ... 221
9.2.2 Physical Interaction in Human Soccer ... 222
9.2.3 Tripping and Getting Tripped Up ... 222
9.2.4 Trunk and Head Impacts ... 224
9.2.5 Limb Impacts ... 225
9.2.6 Being Hit by the Ball ... 227
9.2.7 Secondary Impacts ... 227
9.2.8 Further Aspects ... 228
9.2.9 Injuries from Blunt Impacts with Soft-Tissue ... 228
9.2.10 Analysis of Elbow Checks ... 230
9.3 Robot Joint Protection ... 232
9.3.1 Joint Stiffness and Kicking Force ... 233

9.3.2 Kicking a Soccer Ball with the VS-Joint ... 234
9.4 Robot Performance Improvement ... 238
9.4.1 Kicking in RoboCup ... 239
9.4.2 Required Joint Velocity ... 239
9.4.3 Kicking a Ball with an Elastic Joint ... 240
9.4.4 Optimal Control for Kicking with an Elastic Joint ... 245
9.5 Summary ... 248
References ... 249

10 Intrinsic Joint Compliance ... 253
10.1 Intrinsically Compliant Actuation ... 254
10.2 Design Considerations ... 255
10.3 Joint Design, Modeling, Identification, and Control ... 258
10.3.1 Joint Design ... 259
10.3.2 Torque Characteristics Layout ... 260
10.3.3 Model of the QA-Joint ... 262
10.3.4 Joint Identification ... 264
10.3.5 State Feedback Controller ... 266
10.4 Basic Optimal Control Theory ... 267
10.4.1 Optimal Control of Dynamic Systems ... 267
10.4.2 Singular Control Problems ... 269
10.4.3 The Maximum Principle of Pontryagin ... 269
10.4.4 Bounded State Variables ... 270
10.5 Shooting Methods for Solving MPBVPs ... 271
10.5.1 Single-Shooting ... 271
10.5.2 Multiple-Shooting ... 272
10.6 The Nelder-Mead Simplex-Downhill Algorithm ... 273
10.7 Performance Increase through Joint Compliance ... 275
10.7.1 Maximization of Link Velocity ... 276
10.7.2 Optimal Control for Linear Cases ... 277
10.7.3 Constrained Deflection ... 280
10.7.4 Stiffness Adjustment ... 287
10.7.5 Performance Analysis for the QA-Joint ... 290
10.8 Compliance as a Cornerstone of Safety? ... 298
10.8.1 Sharp Contact ... 299
10.8.2 Blunt Contact ... 300
10.9 Blunt Impact Dynamics ... 302
10.9.1 Head Injury Criterion: Simulation ... 302
10.9.2 Frontal Impact Force ... 303
10.9.3 Maximum HIC for Compliant Joints ... 304
10.9.4 Head Injury Criterion: Experiments ... 307
10.9.5 Joint Protection and Control Performance ... 308
10.10 Collision Detection for VSA ... 309
10.10.1 Generalized Link Side Momentum Observer ... 309
10.10.2 Generalized Joint Momentum Observer ... 309

10.10.3 Collision Detection and Reaction for the QA-Joint 311
10.10.4 Experimental Collision Detection Performance 312
10.11 Summary 313
References 314

11 Considerations for New Robot Standards 317
11.1 Limitations of Existing Safety Standards 319
11.2 Possible Injuries in Robotics: A Synopsis 321
11.3 Extended Abbreviated Injury Scale 323
11.4 Standard Impacts 325
11.4.1 Standard Impact Phases 325
11.4.2 Standard Dummy Impact Tests 326
11.4.3 Crash-Test Dummies for Robot-Human Impacts 329
11.4.4 Possible Extensions 329
11.5 Impact of the Monograph and Next Steps 330
11.6 Summary 333
References 334

12 Conclusion and Outlook 337
12.1 Conclusion 337
12.2 Outlook 342
References 343

A Braking Tests 345

B Maximum Link Velocity for n_c Motor Cycles 348