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# Robot Physical Interaction Through The Combination Of Vision Tactile And Force Feedback Application

**human-robot physical interaction with dynamically stable ...** - keywords: human-robot physical interaction, dynamically stable mobile robots. 1. introduction the ballbot, introduced in [1], is a dynamically stable single spherical wheeled mobile robot capable of omnidirectional motion. unlike statically stable mobile robots, **learning robot objectives from physical human interaction** - physical interaction leads to better robot task performance with less human effort. keywords: physical human-robot interaction, learning from demonstration 1introduction imagine a robot performing a manipulation task next to a person, like moving the person's coffee mug from a cabinet to the table (fig.1). **the benefits of interactions with physically present robots ...** - in applications for which physical manipulation of the environment is not required by a robot, there is a temptation to use software agents or video displays in place of a physically present robot, in order to reduce cost and maintenance. recent human-computer interaction studies have focused on various non-physical, social interactions with **the role of physical embodiment in human-robot interaction** - hypothesis that physical embodiment has a measurable effect on performance and perception of social interactions. support of ... on the perception of robot's social situatedness. in particular, ... interaction with a physical robot, interaction with a remote physical robot (through tele-conferencing), and interaction with a virtual (simulated **project 1: instruments and robots to sense and make use of ...** - of physical interaction between animals and robots (locomotors) and the surrounding terrain (think about what if we wanted to fly an airplane but had no idea how to adjust its wings to generate sufficient lift and not too much drag!). currently the primary approach of robot **motion learning and adaptive impedance for robot control ...** - motion learning and adaptive impedance for robot control during physical interaction with humans elena gribovskaya, abderrahmane kheddar, and aude billard abstract—this article combines programming by demonstration and adaptive control for teaching a robot to physically interact with a human in a collaborative task requiring sharing **human-robot interaction - lab** - human-robot interaction (hri) is the interdisciplinary study of interaction dynamics between humans and robots. researchers and practitioners specializing in hri come from a variety of fields, including engineering (electrical, ... tasks applied to physical rehabilitation post-stroke [32], and for social interaction [122]. **velocity-curvature patterns limit human-robot physical ...** - ently in human-robot and human-human physical interaction, even if the robot moved in human-like patterns [13]. this raises the question whether programming robots according to biological principles of movement can make the human-robot interaction more successful. several studies have investigated how humans interpret **human-robot interaction: a survey** - imate interaction with mobile robots may take the form of a robot assistant, and proximate interaction may include a physical interaction. social interaction includes social, emotive, and cognitive aspects of interaction. in social interaction, the humans and robots interact as peers or companions. importantly, social interactions with robots **natural interaction design of a humanoid robot** - ferland et al., natural interaction design of a humanoid robot from the embodied human-robot interaction, in addition to interdependent effects. in the field of human-computer interaction, "interaction design" is the practice of designing digital products, **physical human robot interaction - tu darmstadt** - physical human-robot interaction mutual learning and adaptation • by shuheikiemoto, heni ben amor, takashi minato, bernhard jung, and hiroshi ishiguro c lose physical interaction between robots and humans is a particularly challenging aspect of robot development. for successful interaction and cooperation, the robot must have the abil-

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