

ISO/TR 23482-2:2019-03 (E)

Robotics - Application of ISO 13482 - Part 2: Application guidelines

| Contents | Page |
|--|------|
| Foreword | iv |
| Introduction | v |
| 1 Scope | 1 |
| 2 Normative references | 1 |
| 3 Terms and definitions | 1 |
| 4 Guidance on the scope of ISO 13482 and gaps or overlaps with other standards | 2 |
| 4.1 General | 2 |
| 4.2 Guidance on the definition of service robots | 2 |
| 4.3 Guidance on the definition of personal care robots | 4 |
| 4.4 Guidance on the distinction between personal care robots and other robots | 5 |
| 5 Concepts in ISO 13482 | 6 |
| 5.1 General | 6 |
| 5.2 Interaction without guards | 6 |
| 5.3 Intended physical contact | 6 |
| 5.4 Autonomous functions | 6 |
| 6 Methodology | 7 |
| 6.1 Risk reduction methodology of ISO 13482 in the context of other safety standards | 7 |
| 6.2 Approach adopted for the working examples | 9 |
| 6.3 Application of wording examples to other robots | 12 |
| 7 Working examples | 12 |
| 7.1 Description policy | 12 |
| 7.2 Example 1 -- Mobile servant robot (high risk) | 13 |
| 7.2.1 Overview | 13 |
| 7.2.2 Risk assessment | 13 |
| 7.2.3 Safety-related control system | 22 |
| 7.3 Example 2 -- Mobile servant robot (low risk) | 23 |
| 7.3.1 Overview | 23 |
| 7.3.2 Risk assessment | 24 |
| 7.3.3 Safety-related control system | 30 |
| 7.4 Example 3 -- Restraint type physical assistant robot | 31 |
| 7.4.1 Overview | 31 |
| 7.4.2 Risk assessment | 32 |
| 7.4.3 Safety-related control system | 40 |
| 7.5 Example 4 -- Person carrier robot | 40 |
| 7.5.1 Overview | 40 |
| 7.5.2 Risk assessment | 41 |
| 7.5.3 Safety-related control functions | 47 |
| 7.6 Example 5 -- Restraint-free type physical assistant robot | 48 |
| 7.6.1 Overview | 48 |
| 7.6.2 Risk assessment | 49 |
| 7.6.3 Safety-related control system | 53 |
| Bibliography | 55 |