

ISO/TR 20218-1:2018-08 (E)

Robotics - Safety design for industrial robot systems - Part 1: End-effectors

Contents		Page
Foreword		iv
Introduction		v
1	Scope	1
2	Normative references	1
3	Terms and definitions	1
4	Risk assessment	2
4.1	General	2
4.2	Limits of the end-effector(s)	3
4.3	Hazard identification	4
4.3.1	General	4
4.3.2	Examples of hazards from end-effectors and workpieces	4
4.4	Risk estimation	4
4.5	Risk evaluation	5
4.6	Residual risks	5
5	Safety requirements and risk reduction	5
5.1	General	5
5.2	Risk reduction measures	5
5.2.1	Shape and surfaces	5
5.2.2	Protective devices and safety-related functions	5
5.2.3	Robot application design	7
5.2.4	Risk reduction measures implemented by the user	7
5.3	Safety-related control system performance	7
5.4	Gripper end-effectors	7
5.4.1	General	7
5.4.2	Grasp-type grippers	8
5.4.3	Vacuum grippers	8
5.4.4	Magnet grippers	8
5.5	Application-specific end-effectors	9
5.5.1	General	9
5.5.2	Examples of applications	9
5.5.3	Risk reduction	9
5.6	End-effectors for hand-guiding robots	10
5.6.1	General	10
5.6.2	Risk reduction	10
5.7	End-effector exchange systems (tool changers)	11
6	Verification and validation	11
7	Information for use	11
7.1	General	11
7.2	Instructions	11
Annex A (informative) Practical examples for end-effector risk assessment		13
Annex B (informative) Examples of gripper designs and their safety performance		18

Annex C (informative) Examples of hazards, their potential origins and consequences	19
Annex D (informative) Examples of hazards by function of the end-effector	22
Bibliography	24