

Quality And Productivity Conference, Proceedings

Cobots in Materials Handling

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In May 1995 Northwestern University and General Motors Corporation began a five year project toward the creation of "Intelligent Assist Devices" (IADs). The project envisioned a class of devices that would improve ergonomic working conditions, product quality, and productivity by applying ideas from robotics to the Manual Assist Devices that are widely used in materials handling.

The project was motivated by issues in automobile final assembly, an area which has seen only limited automation. Human workers bring a number of capabilities to assembly that are difficult to match with automation, such as parts-picking from unstructured environments, identifying defective parts, fitting parts together despite minor shape variation, pushing aside interfering cable bundles or fabric, and many more. Redesigning the assembly process to eliminate the need for such skills is not seen as cost-effective or desirable. However in recent years the size and weight of the components assembled into an automobile body has increased as more subassembly has been done off the main assembly line. Larger subassemblies, and an increasing awareness of the significance and frequency of ergonomic injuries, have led to a need for mechanical assistance of various forms. Manual Assist Devices are typically based on hoists, overhead x-y rail systems, or articulated arms. Their translational motion is usually unpowered, and they incorporate little if any computational logic.

Manual Assist Devices increase the friction and inertia that a worker must cope with in completing a task. It is not uncommon for an assist device to have a moving mass ten times that of its payload. Where motion of the payload must be restricted to avoid collisions, mechanical guides or stops are used. For sophisticated insertions, shaped guide rails may be constructed to define the path of the payload as it approaches its assembly location. Such manual assist devices can offer ergonomic benefits, but they also have significant drawbacks in maneuverability, productivity, and lack of programmability.

In response to the limitations of Manual Assist Devices, a central goal of the GM/Northwestern project was to find a way of implementing large-scale virtual surfaces, which we proposed as a primary form of interface between human worker and computer in Intelligent Assist Devices. Virtual surfaces promised to provide physical guidance for workpart motion, without requiring that the guiding surface be physically embodied as a solid object such as a rail.

The development of cobots⁵ provided a programmable means of setting up large-scale virtual surfaces. When an operator pushes a payload up against a virtual surface established by a cobot, the payload's motion is confined to follow that surface, just as if it had run into a frictionless guide rail. When the payload is pulled away from the virtual surface, operator and payload motion is unconstrained ("free mode").

Cobots in materials handling applications are thus a departure from the industrial paradigm of independently competent robots isolated from human contact. They also differ also from telerobotics, in which a human operator controls a remote manipulator through what is essentially an information-only

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⁵ Nonholonomic Haptic Display, J. Edward Colgate, Michael Peshkin, Witaya Wannasupphrasit, Proceedings of the IEEE 1996 Int'l Conference on Robotics and Automation, Minneapolis (Best Conference Paper Award)

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