



## A haptic guidance generic approach

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### ► To cite this version:

Alexis Boulay, David Daney, Margot Vulliez, Romain Schmitt, Arthur Bonastre. A haptic guidance generic approach. JJCR 2023 - Journée des Jeunes Chercheurs en Robotique, Oct 2023, Moliets-et-Maâ, France. hal-04334395

**HAL Id: hal-04334395**

**<https://inria.hal.science/hal-04334395>**

Submitted on 11 Dec 2023

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# A haptic guidance generic approach

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## Context

**Teleoperation** : Allow a human to take control of the robot for remote operation.



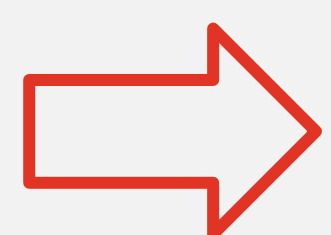
How to ensure interaction performances?

↳ **Shared autonomy** : Enable some robot autonomy for specific simple tasks.



How to assist a human with more difficult tasks ?

↳ **Haptic guidance** : Generate a force that guides the user to follow a behaviour.

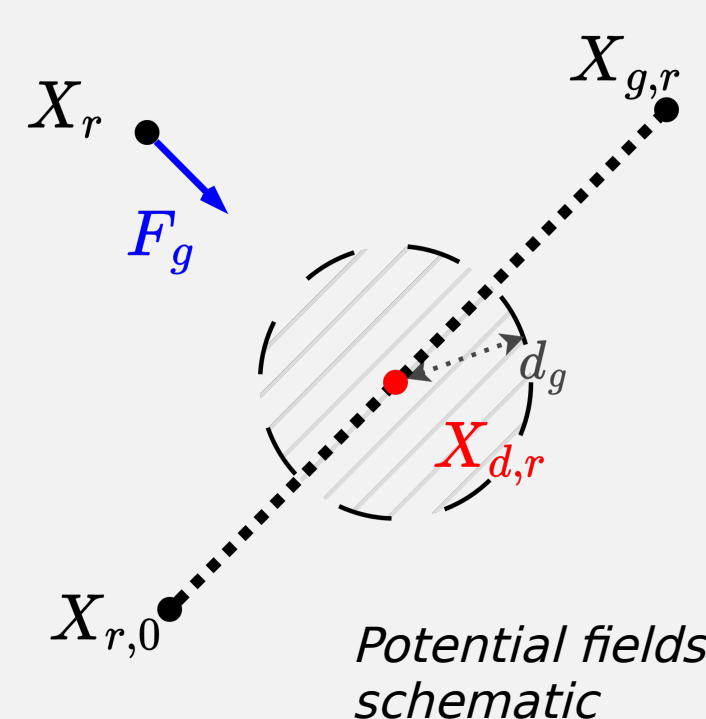


What are the different computation methods for haptic guidance and how can a generic approach be defined ?

## Potential fields

**Attract or repel operator to a position**

- Allow multiple targets
- Free space exploration
- Local minimum

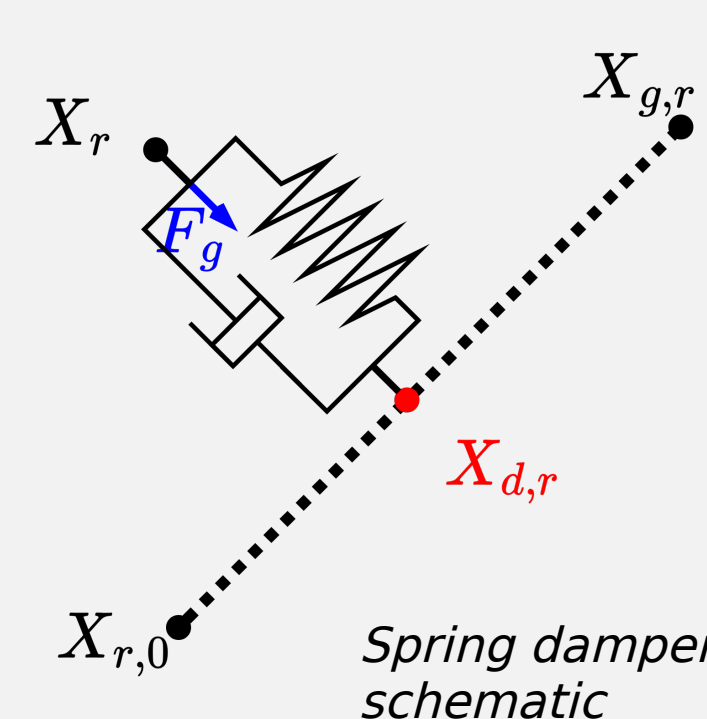


$$\Rightarrow f_{PF}(d_{d,r}) = \begin{cases} \frac{d_{d,r}^2}{d_g^2} & \text{if } d_{d,r} \leq d_g \\ \frac{1}{d_{d,r}} & \text{else} \end{cases}$$

## Spring damper

**Attach operator to a path**

- Unique target
- Allow obstacle avoidance
- Stable

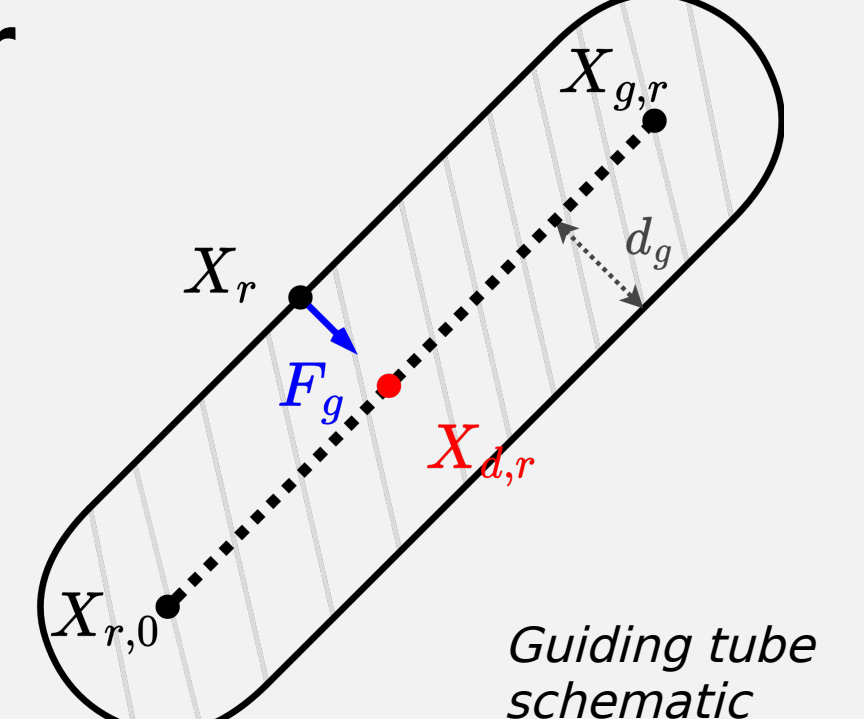


$$\Rightarrow f_{SD}(d_{d,r}) = d_{d,r}$$

## Guiding tube

**Prevent operator from leaving an area**

- Multiple geometry
- Limited free space
- Stable

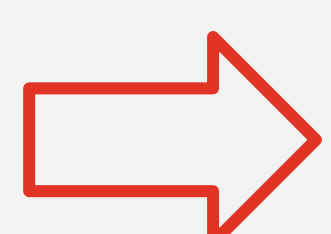


$$\Rightarrow f_{GT}(d_{d,r}) = \begin{cases} 0 & \text{if } d_{d,r} \leq d_g \\ (d_{d,r} - d_g) & \text{else} \end{cases}$$

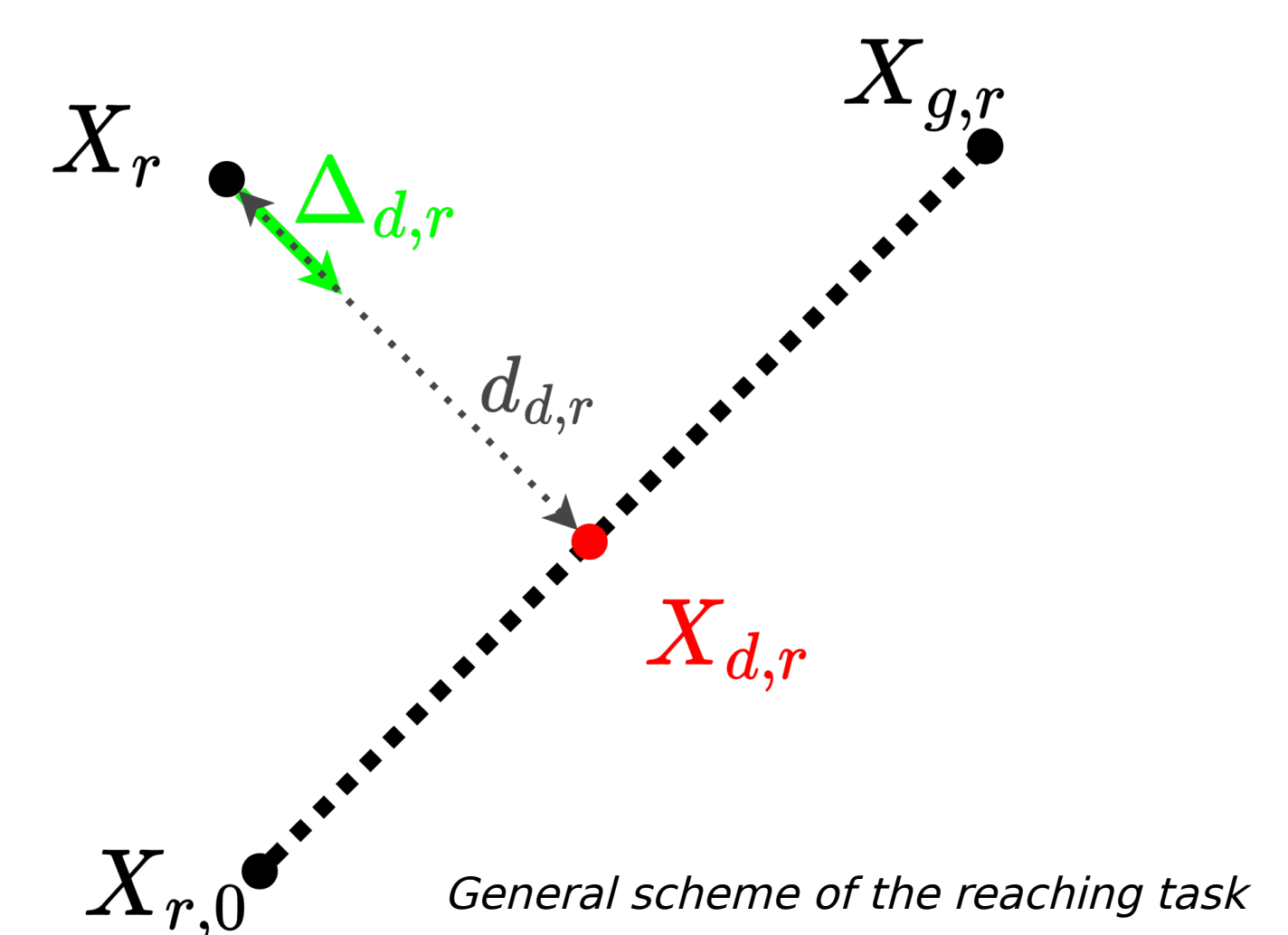
## Virtual fixture

**Geometric constraint used to generate a haptic guidance**

- $f(d_{d,r})$  is the **attraction function** associated with the generic guidance equation, it depends of the distance  $d_{d,r}$  between  $X_r$  the robot position and  $X_{d,r}$  the desired position
- $K_g$  and  $B_g$  are generic **impedance** and **damping gains** that can be designed to constrain some directions
- $\dot{X}_h$  is the **haptic device velocity**, it is used for damping to obtain a better reactivity



$$F_g = K_g f(d_{d,r}) \Delta_{d,r} - B_g \dot{X}_h$$

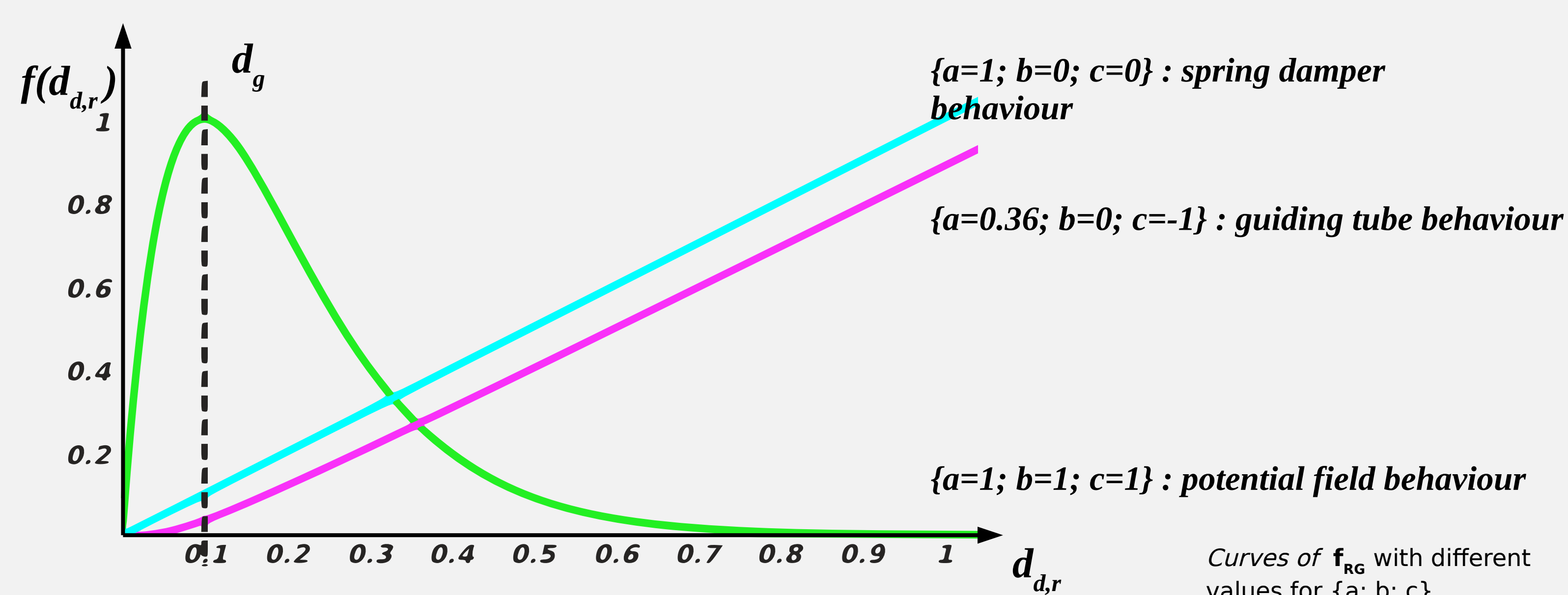


## Ruling guidance

Use of a generic, parameterised and continuous attraction function



$$f_{RG}(d_{d,r}) = a \frac{d_{d,r}}{(d_g)^b} \exp(1 - (\frac{d_{d,r}}{d_g})^c)$$



- **Continuous** change between the different types of guidance
- Exploration of **intermediate guidance**
- Provide **optimal guidance** relative to the task, the operator and the environment

## Experiment

A future experiment will implement and compare different parameterisation of the ruling guidance, and try to define the optimal guidance considering, task, environment and user.

It consists of reaching a plant position in a vertical farm in different scenarios.

