

11. Adaptive Human-Robot Physical Interaction for Robot Coworkers	297
J. Ueda, W. Gallagher, A. Moualeu, M. Shinohara, K. Feigh	
1. Introduction	297
2. Haptic Stability	298
3. Human Operator Modeling	300
4. Haptic Assist Control	303
5. System Integration	308
6. System Validation and Experimental Evaluation	313
7. Limitations and Solution Approaches	324
8. Conclusion	325
Appendix A Crowninshield's Optimality Principle	326
Appendix B Performance Scores Calculation	327
Acknowledgments	327
References	328
<i>Index</i>	335

3. BMI for Assistive Robotics	196
4. BMI for Rehabilitation Robotics	202
5. Conclusion	207
Acknowledgments	208
References	208
8. Intention Inference for Human-Robot Collaboration in Assistive Robotics	217
H.C. Ravichandar, A. Dani	
1. Background	217
2. Research Challenges and Solution Approach	220
3. Applications	230
4. Discussion	238
5. Conclusion	240
Appendix A Kalman Filter Implementation	242
Appendix B Analytical Jacobian and Hessian of the NN	242
Appendix C Gradient of the Q Function	243
Appendix D Stability Analysis	244
References	246
9. Biomechanical HRI Modeling and Mechatronic Design of Exoskeletons for Assistive Applications	251
S. Bai, S. Christensen	
1. Introduction	251
2. Challenges in Exoskeleton Design	253
3. Biomechanical Modeling	257
4. Development of HRI Model	259
5. Design Examples	259
6. Conclusions	270
Acknowledgments	270
References	270
10. Psychological Modeling of Humans by Assistive Robots	273
A. Wagner, E. Briscoe	
1. Introduction	273
2. Dimensions of Human Characterization	275
3. Constructing Behavioral Models for HRI	279
4. Economic Decision-Making Models	281
5. Inferring Psychological Models	288
6. Conclusions	292
References	292

4. Personalized Modeling for Home-Based Postural Balance Rehabilitation	111
M. Hayashibe, A. González, P. Fraisse	
1. Introduction	111
2. Home-Based Postural Balance Rehabilitation	112
3. Body Segment Parameters	114
4. Estimating Center of Mass Position for Human Subjects	115
5. Method	118
6. Results	124
7. Discussion	132
8. Conclusion	133
References	133
5. Modeling and Dynamic Optimization of a Hybrid Neuroprosthesis for Gait Restoration	139
N. Sharma, N. Kirsch	
1. Introduction	139
2. Dynamic Model	141
3. Dynamic Optimization	147
4. Simulations and Results	149
5. Conclusion and Future Work	154
Appendix	155
References	157
6. Soft Wearable Robotics Technologies for Body Motion Sensing	161
Y.-L. Park	
1. Body Motion Sensing	161
2. Soft Artificial Skin Using Embedded Conductive Liquids	165
3. Strain-Sensitive Conductive Polymers	173
4. Fiber Optic Wearable Sensors for Motion Sensing	176
5. Conclusions and Future Developments	180
References	181

Part II Modeling of Human Cognitive/Muscular Skills and Their Applications **185**

7. Noninvasive Brain Machine Interfaces for Assistive and Rehabilitation Robotics: A Review **187**

G. Lisi, J. Morimoto

1. Introduction	187
2. Brain Machine Interfaces	188

CONTENTS

<i>Contributors</i>	<i>ix</i>
<i>Motivation</i>	<i>xi</i>
<i>About This Book</i>	<i>xiii</i>

Part I Modeling of Human Musculoskeletal System/ Computational Analysis of Human Movements and Their Applications	1
1. Implementation of Human-Like Joint Stiffness in Robotics Hands for Improved Manipulation	3
A. Deshpande, T. Niehues, P. Rao	
1. Introduction	3
2. Modeling of Joint Stiffness	4
3. Multifinger Manipulation With Passive Joint Stiffness	25
4. Discussion	33
References	34
2. A Review of Computational Musculoskeletal Analysis of Human Lower Extremities	37
A. Alamdari, V.N. Krovi	
1. Introduction	37
2. Human Walking Gait Cycle	39
3. Biomechanics of Normal Human Walking	42
4. Quantitative Human Walking Models	43
5. Computational Musculoskeletal Analysis Interaction With Articulated Systems	60
6. Conclusion	66
References	67
3. EMG-Controlled Human-Robot Interfaces: A Hybrid Motion and Task Modeling Approach	75
N. Bu, T. Tsuji, O. Fukuda	
1. Introduction	75
2. EMG Motion Classification	78
3. Task Modeling for Human Interfaces	86
4. An EMG-Controlled Human-Robot Interface Using Task Modeling	92
5. Discussion and Summary	102
References	104