

# 4. Risk Assessment

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## Description

The risk assessment is a requirement that shall be performed for the application. The application risk assessment is the responsibility of the integrator. The user can also be the integrator.

The robot is partly completed machinery, as such the safety of the robot application depends on the tool/end effector, obstacles and other machines. The party performing the integration must use ISO 12100 and ISO 10218-2 to conduct the risk assessment. Technical Specification ISO/TS 15066 can provide additional guidance for collaborative applications. The risk assessment shall consider all tasks throughout the lifetime of the robot application, including but not limited to:

- Teaching the robot during set-up and development of the robot application
- Troubleshooting and maintenance
- Normal operation of the robot application

A risk assessment must be conducted **before** the robot application is powered on for the first time. The risk assessment is an iterative process. After physically installing the robot, verify the connections, then complete the integration. A part of the risk assessment is to determine the safety configuration settings, as well as the need for additional emergency stops and/or other protective measures required for the specific robot application.

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## Safety configuration settings

Identifying the correct safety configuration settings is a particularly important part of developing robot applications. Unauthorized access to the safety configuration must be prevented by enabling and setting password protection.



### WARNING

Failure to set password protection can result in injury or death due to purposeful or inadvertent changes to configuration settings.

- Always set password protection.
- Set up a program for managing passwords, so that access is only by persons who understand the effect of changes.

Some safety functions are purposely designed for collaborative robot applications. These are configurable through the safety configuration settings. They are used to address risks identified in the application risk assessment.

The following limit the robot and as such can affect the energy transfer to a person by the robot arm, end effector and workpiece.

- **Force and power limiting:** Used to reduce clamping forces and pressures exerted by the robot in the direction of movement in case of collisions between the robot and the operator.
- **Momentum limiting:** Used to reduce high transient energy and impact forces in case of collisions between robot and operator by reducing the speed of the robot.
- **Speed limitation:** Used to ensure the speed is less than the configured limit.

The following orientation settings are used to avoid movements and reduce exposure of sharp edges and protrusions to a person.

- **Joint, elbow and tool/end effector position limiting:** Used to reduce risks associated with certain body parts: Avoid movement towards head and neck.
- **Tool/end effector orientation limiting:** Used to reduce risks associated with certain areas and features of the tool/end effector and work-piece: Avoid sharp edges being pointed towards the operator, by turning the sharp edges inward towards the robot.

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## Stopping performance risks

Some safety functions are purposely designed for any robot application. These features are configurable through the safety configuration settings. They are used to address risks associated with the stopping performance of the robot application.

The following limit the robot stopping time and stopping distance to ensure stopping will occur before reaching the configured limits. Both settings automatically affect the speed of the robot to ensure the limit is not exceeded.

- **Stopping Time Limit:** Used to limit the stopping time of the robot.
- **Stopping Distance Limit:** Used to limit the stopping distance of the robot.

If either of the above is used, there is no need for manually performed periodic stopping performance testing. The robot safety control does continuous monitoring.

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If the robot is installed in a robot application where hazards cannot be reasonably eliminated or risks cannot be sufficiently reduced by use of the built-in safety-related functions (e.g. when using a hazardous tool/end effector, or hazardous process), then safeguarding is required. See ISO 10218-2.



## WARNING

Failure to conduct a application risk assessment can increase risks.

- Always conduct an application risk assessment for foreseeable risks and reasonably foreseeable misuse.

For collaborative applications, the risk assessment includes the foreseeable risks due to collisions and to reasonably foreseeable misuse.

The risk assessment shall address:

- Severity of harm
- Likelihood of occurrence
- Possibility to avoid the hazardous situation

## Potential Hazards

Universal Robots identifies the potential significant hazards listed below for consideration by the integrator. Other significant hazards can be associated with a specific robot application.

- Penetration of skin by sharp edges and sharp points on tool/end effector or tool/end effector connector.
- Penetration of skin by sharp edges and sharp points on nearby obstacles.
- Bruising due to contact.
- Sprain or bone fracture due to impact.
- Consequences due to loose bolts that hold the robot arm or tool/end effector.
- Items falling out of, or flying from the tool/end effector, e.g. due to a poor grip or power interruption.
- Mistaken understanding of what is controlled by multiple emergency stop buttons.
- Incorrect setting of the safety configuration parameters.
- Incorrect settings due to unauthorized changes to the safety configuration parameters.

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## 4.1. Pinch Hazard

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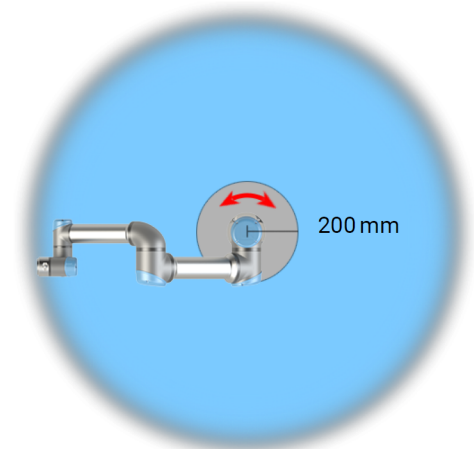
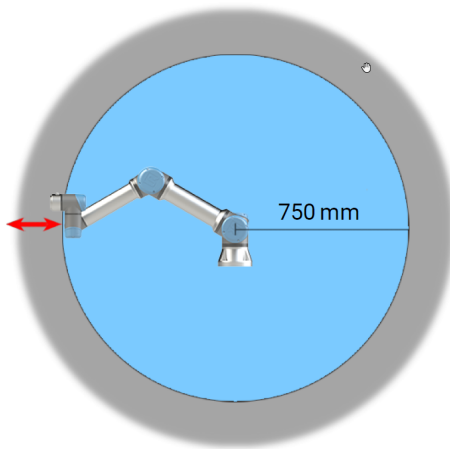
## Description

You can avoid pinching hazards by removing obstacles in these areas, by placing the robot differently, or by using a combination of safety planes and joint limits to eliminate the hazards by preventing the robot moving into this area of its workspace.



### CAUTION

Placing the robot in certain areas can create pinching hazards that can lead to injury.



*Due to the physical properties of the robot arm, certain workspace areas require attention regarding pinching hazards. One area (left) is defined for radial motions when the wrist 1 joint is at least 750 mm from the base of the robot. The other area (right) is within 200 mm of the base of the robot, when moving tangentially.*

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