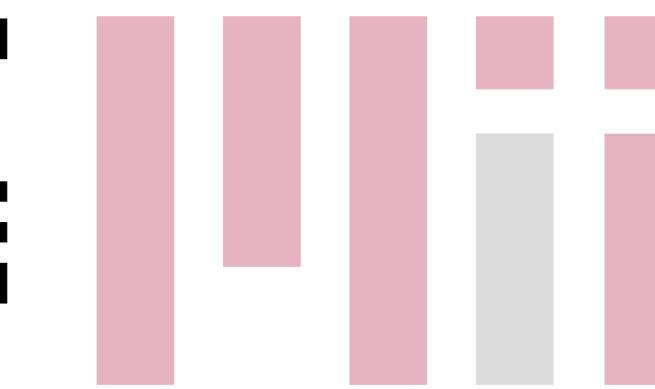


Provably Safe and Efficient Motion Planning with Uncertain Human Dynamics

Shen Li, Nadia Figueroa, Ankit Shah, Julie A. Shah



<https://safe-dressing.github.io/>



Motivations

- Ensure human physical safety,
- without unnecessarily impacting task efficiency.

Contributions

- Planner with probabilistic safety guarantee.
- Define safety as collision avoidance OR safe impact during collisions.

