Claims

1. An assistance robot comprising:

a base configured to rest on a floor surface;

a holding member configured to hold an upper body of a care receiver;

a driving device configured to support the holding member so as to be movable in an up-down direction and a front-rear direction and to move the holding member along multiple different movement paths; and

a control device configured to control operation of the driving device by executing operation processing for moving the holding member during a sitting operation of the care receiver sitting on a seat based on, among the multiple sitting paths, the sitting path corresponding to the sitting operation,

wherein

the operation processing based on the sitting path includes

a retracting process for retracting the holding member and lowering or raising the holding member to a fixed sitting position at which a buttock portion of the care receiver is positioned at a specified height from the floor surface and above the seat, and

a lowering process for lowering the holding member from the fixed sitting position until the care receiver is sitting on the seat,

wherein

the retracting process includes retracting the holding member on a movement path set based on the fixed sitting position and a position of the holding member while the operation processing is being performed based on the sitting path, and

the lowering process includes lowering the holding member on a fixed movement path.

2. The assistance robot according to claim 1, wherein

the driving device includes

a raising and lowering section configured to move in an up-down direction with respect to the base, and

a pivoting section configured to move the holding member in a front-rear direction of the base with respect to the raising and lowering section and to rotate the holding member around an axis parallel to a left-right direction of the base,

wherein

the retracting process includes retracting the holding member to a retract end in a movement region of the holding member in accordance with operation of the pivoting section, and

the lowering processing includes lowering the holding member by only operation of the raising and lowering section.

3. The assistance robot according to any one of the claims 1 to 2, wherein

the lowering process includes lowering the holding member such that the buttock portion of the care receiver is lowered perpendicularly towards the seat.

4. The assistance robot according to any one of the claims 1 to 3, wherein

the specified height of the fixed sitting position, in a case in which the seat is at a maximum height that can be handled by the assistance robot, is set to at least a height of the holding member at which the buttock portion of the care

receiver contacts the seat.

5. The assistance robot according to any one of the claims 1 to 4, wherein

the control device, during the operation processing based on the sitting path, executes the retracting process and the lowering process in a case in which a current position of the holding member is forward of the fixed sitting position, and executes only the lowering processing in a case in which the current position of the holding member is not forward of the fixed sitting position.

6. The assistance robot according to any one of the claims 1 to 5, further comprising

a sitting switch configured to receive an instruction for an execution request of the sitting operation,

wherein

the control device is configured to control operation of the driving device while the execution request of the sitting operation is being input via the sitting switch.