Claims

1. Robot (1) with a mobile base element (6) and with at least one multi-articulated robot arm (10), which is designed to interact directly or indirectly with a human being,
as well as with at least one telemonitoring device (2) and/or at least one telediagnostic device (3) and/or at least one telemetry device (4) and/or at least one teletherapy device (5),
wherein the robot arm (10) is designed to be compliant-controlled.

2. Robot according to claim 1, wherein said at least one multi-articulated robot arm (10) is adapted to actuate and/or to cooperate with said at least one telemonitoring device (2) and/or at least one telediagnostic device (3) and/or at least one telemetry device (4) and/or at least one teletherapy device (5).

3. Robot according to claim 1 or 2, wherein the telemonitoring device (1) comprises at least one sensor (14) for detecting vital parameters and wherein the robot arm (10) is adapted to guide the sensor (14) to a corresponding measuring point of a body.

4. Robot according to claim 1 of 2, wherein the telediagnostic device (3) comprises at least one ultrasound probe (16) and wherein the robot arm (10) is adapted to guide the probe (16) to a corresponding recording site of a body and/or along the corresponding recording site.

5. Robot according to claim 3 or 4, wherein the telemetry device (4) is adapted to transmit the data detected by means of the sensors (14) and/or the probes (16) to an external receiving

point.

6. Robot according to claims 1 to 5, wherein the teletherapy device (5) comprises an audio-visual device (9).

7. Robot according to any one of claims 1 to 6, wherein the at least one robot arm (10) has a proximal base (12) and a distal free end (13).

8. Robot according to claim 3 or 4 and 7, wherein the distal end (13) is adapted to grip the sensors (14) and/or probes (16).

9. Robot according to claim 3 or 4 and 7, wherein the distal end (13) integrally comprises the sensors (14) and/or probes (16).

10. Robot according to claim 7, wherein a torso (7) is provided which is arranged on the mobile base element (6), at which the proximal base (12) of the robot arm (10) is guided displaceably, in particular linearly.

11. Robot according to claim 10, wherein a head (8) is provided on the torso (7).

12. Robot according to claim 10 or 11, wherein the teletherapy device (5) is provided in the torso (7) and/or in the head (8).

13. Robot according to claim 3 or 4, wherein the robot arm (10) is configured such that the guiding of the sensors (14) and/or the probes (16) relative to the measuring/recording point is performed by force-controlled and/or impedance-controlled translational and/or rotational and/or tilting movements.

14. Robot according to claim 13, wherein the robot arm (10) is configured to define a contact force in the region of the measuring/recording point by achieving or exceeding at least one

of a predetermined threshold condition for a torque acting at the distal end (13) and/or a force acting at the distal end (13), and/or achieving or exceeding a provided force/torque signature and/or a position/velocity signature at the distal end (13).

15. Robot according to claim 13 or 14, wherein the robot arm (10) is remotely controllable.

16. Robot according to claims 3 to 15, in which the sensors (14) and/or probes (16) can be deposited on or in the torso (7).

17. Robot according to any one of the preceding claims, wherein the robot (1) comprises at least one control unit (18) which is designed to enable machine learning of the robot (1) in the context of interaction with humans.