

ROBOT ARM AND ROBOT WRIST

FIELD OF THE INVENTION

The invention relates to a robot arm, having a plurality of arm links, each connected via actuator-drivable joint connections, wherein the proximal arm link of the robot arm can be connected to a robot body via a joint connection, and the distal arm link of the robot arm can be connected to a mountable effector via a joint connection. At a minimum, the last three joint connections of the distal end of the robot arm each enable rotation about an axis of rotation. Such robot arms are known in the prior art.

The invention further relates to a robot wrist, having three actuator-drivable wrist joint connections which are connected in series via two wrist links, wherein the proximal wrist link of the robot wrist can be connected to a robot arm via one of the wrist joint connections, the distal wrist link of the robot wrist can be connected to an effector via another of the wrist joint connections, and each of the three wrist joint connections enables a movement about a wrist axis of rotation assigned to the same. Such robot wrists are also known in the prior art.

Finally, the invention relates to a robot, having a robot arm or a robot wrist.

SUMMARY OF THE INVENTION

The problem addressed by the invention is that of designing the robot arm or the robot wrist in such a manner that the handling of the robot arm and/or the robot wrist, in particular for manipulations of objects or the environment above and/or on a work surface, is improved.

The invention is apparent in the features of the independent claims. Advantageous developments and refinements are the subject matter of the dependent claims. Other features, possible applications, and advantages of the invention will become apparent

from the following description, along with the explanation of embodiments of the invention, which are illustrated in the figures.

To address a first aspect of the problem, a robot arm is suggested which has a number N of actuator-drivable joint connections GV_n , which are connected in series via arm links GL_i , where $n = 1, 2, \dots, N$, $i = 1, 2, \dots, N-1$, and $N \geq 6$, wherein the proximal arm link GL_1 of the robot arm can be connected to a robot body via the joint connection GV_1 , the distal arm link GL_{N-1} of the robot arm can be connected to an effector E via the joint connection GV_N , the arm links GL_{N-1} and GL_{N-2} are connected via the joint connection GV_{N-1} and the arm links GL_{N-2} and GL_{N-3} are connected via the joint connection GV_{N-2} , and each of the joint connections GV_N , GV_{N-1} , GV_{N-2} enables a movement about an axis of rotation $R_{GV,N}$, $R_{GV,N-1}$, $R_{GV,N-2}$ assigned to the same.

The distal joint connections GV_N , GV_{N-1} , GV_{N-2} , together with the joint connections GL_{N-2} , GL_{N-1} , form a kind of "wrist," which enables an orientation of the effector E in three degrees of freedom relative to the previous joint connections $GL_{N-3} \dots$

The proposed robot arm is characterized in that the robot arm is designed in such a manner that the axes of rotation $R_{GV,N-2}$ and $R_{GV,N-1}$ intersect at an angle in the range from 50 to 130° , or the axes of rotation $R_{GV,N-2}$ and $R_{GV,N-1}$ have a minimum spacing $A1$ from each other in the range from 1 to 20 mm, the axis of rotation $R_{GV,N}$ is arranged radially at a constant distance $D1$ to the axis of rotation $R_{GV,N-1}$, and in the joint connection GV_{N-1} to detect a force or a torque about the axis of rotation $R_{GV,N-1}$ (and/or the effective torque about the axis).

The minimum spacing of the axes of rotation $R_{GV,N-2}$ and $R_{GV,N-1}$ is preferably 2 mm, 5 mm, 7 mm, 10 mm, 12 mm, 15 mm or 17 mm. The range of the angle at which the axes of rotation $R_{GV,N-2}$ and $R_{GV,N-1}$ intersect is preferably 50 to 130° , 60 to 120° , 70 to 110° , 80 to 100° or 85 to 95° .

A known force or torque sensor can be present on the output end to detect the force or the torque. However, the sensor can also be designed as a direct drive. In the latter case, the direct drive can be the drive and the sensor simultaneously. Torque is typically estimated by measuring motor current and using known physical

relationships. However, a combination of both is explicitly not excluded (direct drive and an output-end sensor to measure acting internal and external forces even more accurately).

The aim in this case is to produce improved sensitivity to acting torques and forces, in particular opposing acting contact forces, via the acting lever.

The number N is advantageously equal to 6 or 7 or 8. It is particularly preferred that the robot arm is, in the latter case ($N = 7$), connected to the robot body by means of the proximal arm link GL_1 via the likewise actuator-drivable joint connection GV_1 , such that the robot arm including the effector E can be controlled about a total of 7 axes R_{GV1} , R_{GV2} , R_{GV3} , R_{GV4} , R_{GV5} , R_{GV6} , and R_{GV7} . The three distal joint connections GV_5 , GV_6 , GV_7 , together with the axes of rotation R_{GV5} , R_{GV6} and R_{GV7} and the arm links GL_5 and GL_6 , along with the effector E , can be collectively referred to as a manner of "wrist." The 7-axis ($N = 7$) robot arm enables three-dimensional positioning and three-dimensional orientation of the end effector E in the working space of the robot. This means that the robot arm has a working space in which its effector E can reach every point in space in any orientation.

The proximal arm links (for example, for $N = 6$: GL_1 , GL_2 and GL_3) are advantageously long arm links, for three-dimensional positioning of the effector E in the working space, to enable positioning of the effector E in the largest possible working space. The distal arm links (for example, for $N = 6$: GL_4 , GL_5 and GL_6) are advantageously short arm links, to bring the effector E into a desired orientation in a small space.

The effector (tool) E can be selected from a variety of tools, by way of example a gripper, welding gun, welding tongs, adhesive nozzle, painting nozzle, drilling/milling head, measuring tool, laser cutting head, water jet cutting head, etc., according to the task and requirements. The effector E can be connected directly to the joint connection GV_N , or can be connected to the joint connection GV_N via a (rigid) intermediate piece, such as an adapter, for example. The intermediate piece can be designed as a further arm link.

The proposed robot arm has multiple advantages. The spacings $D1$ and $A1$ result in

levers which enable improved measurement of external forces and/or torques in almost all configurations of the angular joint connections. As such, the spacing D1 enables a detection of external forces and/or torques by means of the sensor present in the joint connection GV_{N-1} , even when a force acts along the axis of rotation $R_{GV,N}$. Recognition of external torques about the axis of rotation $R_{GV,N}$ is also possible. Furthermore, in the proposed robot arm, there are no classical singularities in the detection of external torques or forces in the wrist (= distal joint connections GV_N , GV_{N-1} , GV_{N-2} with the arm links GL_{N-2} , GL_{N-1} and the effector E), since the last two axes of rotation $R_{GV,N-1}$ and $R_{GV,N}$ do not intersect. A further advantage relates to a re-configuration of the wrist. This can be achieved to a great extent by moving the wrist alone, such that there is no need to move the entire robot arm.

It is advantageous that a movement of the robot arm with the effector E about the so-called tool center point (TCP = a reference point which is defined at a suitable location on the tool/effector) is possible, particularly in all robot arm configurations, if the axes of rotation $R_{GV,N-2}$ and $R_{GV,N}$ intersect. Even if there is no intersection, the closer the axes of rotation $R_{GV,N-2}$ and $R_{GV,N}$ are arranged to each other in a current robot arm configuration, the easier it is to execute the rotation about the tool center point.

Considering application scenarios of the robot arm in which the robot arm, including the effector E, is used to execute manipulations of an object on and/or above a working surface (such as a table top) in the immediate environment of the robot body (within the working range of the robot), the proposed robot arm advantageously enables a simple rotation around the tool center point. This means that this rotation is largely possible as a result of the movement of the wrist alone, such that it is not necessary to move the entire robot arm for a desired movement in the task space.

Overall, the "wrist" of the proposed robot arm and/or the entire robot arm enables, due to the effective projection of the external forces and torques into the joint torques, an improved detection of acting external forces and torques, and particularly - for a manual guidance of the wrist, by way of example for direct input (patterning, teaching) of movement processes - an improved handling of objects, particularly for work on and/or above a work surface, and finally an improved and finer control of object manipulations, and for collision avoidance of the robot arm with objects in an

environment.

An advantageous development of the robot arm is characterized in that the robot arm is designed in such a manner that, in each robot arm configuration, a projection of the axis of rotation $R_{GV,N}$ (projected axis of rotation $R_{GV,N}^*$) onto a plane spanned by axes of rotation $R_{GV,N-2}$ and $R_{GV,N-1}$ forms an angle in the range from 50° to 130° with the axis of rotation $R_{GV,N-1}$.

An advantageous development of the robot arm is characterized in that the axis of rotation $R_{GV,N-2}$ and the axis of rotation $R_{GV,N-1}$ form an angle of 90° , and/or the projection of the axis of rotation $R_{GV,N}$ (projected axis of rotation $R_{GV,N}^*$) onto the plane spanned by the axes of rotation $R_{GV,N-2}$ and $R_{GV,N-1}$ forms an angle of 90° with the axis of rotation $R_{GV,N-1}$. Tolerances of $\pm 2^\circ$ or $\pm 5^\circ$ advantageously apply for the indicated angles - in particular, for the angle of 90° .

An advantageous development of the robot arm is characterized in that the spacing $D1$ is selected to be in the range from 10 mm to 50 cm, and advantageously 15 mm, 20 mm, 50 mm, 75 mm, 1 cm, 5 cm, 10 cm, 15 cm, 20 cm, 25 cm, 30 cm, 35 cm, 40 cm, or 45 cm.

An advantageous development of the robot arm is characterized in that the axes of rotation $R_{GV,N-2}$ and $R_{GV,N-1}$ form an angle of 90° , and/or the projection of the axis of rotation $R_{GV,N}$ onto the plane spanned by the axes of rotation $R_{GV,N-2}$ and $R_{GV,N-1}$ forms an angle of 90° with the axis of rotation $R_{GV,N-1}$.

An advantageous development of the robot arm is characterized in that the section of the robot arm comprising the joint connections GV_{N-2} , GV_{N-1} and GV_N , the arm links GL_{N-2} and GL_{N-1} , and the effector E mounted on the joint connection GV_N is designed in such a manner that a movement of the arm links GL_{N-1} and the effector E about the axis of rotation $R_{GV,N-1}$ is possible without hindrance in any pose.

An advantageous development of the robot arm is characterized in that the joint connection GV_N has a sensor for detecting a force or torque about the axis of rotation

$R_{GV,N}$, and/or the joint connection GV_{N-2} has a sensor for detecting a force or torque about the axis of rotation $R_{GV,N-2}$. Particularly advantageously, all joint connections GV_n are designed for detecting forces and/or torques about their respective axes of rotation R_{GVn} . This enables a more accurate detection of dynamically acting internal and external forces and torques of the robot arm, which improves, for example, a control of the robot arm and a collision detection along the robot arm - for example, supported by appropriate model-based estimation methods.

An advantageous development of the robot arm is characterized in that the robot arm is designed in such a manner that the axes of rotation R_{GV1} and R_{GV2} intersect at an angle in the range from 50 to 130°, the axes of rotation R_{GV2} and R_{GV3} intersect at an angle in the range from 50 to 130°, the axis of rotation R_{GV4} is arranged radially at a constant spacing $D2$ from the axis of rotation R_{GV3} , and the axes of rotation R_{GV4} and R_{GV5} intersect at an angle in the range from 50 to 130°.

An advantageous development of the robot arm is characterized in that the robot arm is designed in such a manner that the axes of rotation R_{GV1} and R_{GV2} intersect at an angle in the range from 50 to 130°, the axes of rotation R_{GV2} and R_{GV3} intersect at an angle in the range from 50 to 130°, the axes of rotation R_{GV3} and R_{GV4} intersect at an angle in the range from 50 to 130°, and the axis of rotation R_{GV5} is arranged radially at a spacing $D3$ from the axis of rotation R_{GV4} .

An advantageous development of the robot arm is characterized in that the robot arm is designed in such a manner that the axes of rotation R_{GV1} and R_{GV2} intersect at an angle in the range from 50 to 130°, the axes of rotation R_{GV2} and R_{GV3} intersect at an angle in the range from 50 to 130°, the axis of rotation R_{GV4} is arranged radially at a constant spacing $D4$ from the axis of rotation R_{GV3} , and the axis of rotation R_{GV5} is arranged at a spacing $D5$ from the axis of rotation R_{GV4} .

The above developments relate in particular to the structural design of the robot arm, starting from its proximal end. The different structural variants of the robot arm proposed above are to be selected depending on the purpose and task, and enable optimal detection of external forces and torques acting along the robot arm, as well as a sensitive execution of movements.

According to the second aspect of the invention, the invention relates to a robot wrist, having three actuator-drivable wrist joint connections HGV_n which are connected in series via two wrist links HGL_i , where $n = 1, 2, 3$ and $i = 1, 2$, wherein the proximal wrist link HGL_1 of the robot wrist can be connected to a robot arm via the wrist joint connection HGV_1 , the distal wrist link HGL_2 of the robot wrist can be connected via the wrist joint connection HGV_3 to an effector E , the wrist links HGL_2 and HGL_1 are connected via the wrist joint connection HGV_2 , and each of the wrist joint connections HGV_1 , HGV_2 , HGV_3 enables a movement about a wrist axis of rotation $HR_{GV,1}$, $HR_{GV,2}$, $HR_{GV,3}$ assigned to the same.

The proposed robot wrist is characterized in that the robot wrist is designed such that the wrist axes of rotation $HR_{HGV,1}$ and $HR_{HGV,2}$ intersect at an angle in the range from 50 to 130° or the wrist axes of rotation $HR_{HGV,1}$ and $HR_{HGV,2}$ have a minimum spacing $A1$ in the range from 1 to 20 mm from each other, the wrist axis of rotation $HR_{HGV,3}$ is arranged radially at a constant spacing $D1$ from the wrist axis of rotation $HR_{HGV,2}$, and a sensor for detecting a force or a torque about the wrist axis of rotation $HR_{HGV,2}$ is present in the wrist joint connection HGV_2 .

The proposed robot wrist enables a three-dimensional orientation of the effector E . A robot arm which can be connected to the robot wrist also enables a three-dimensional positioning of the wrist and/or the effector E in a working space of the robot (robot arm and robot wrist and effector E). The robot wrist, consisting of the distal three wrist joint connections, enables sensitive interaction with humans and/or objects, and/or the handling of objects, wherein the wrist is designed - as a result of the arrangement of the wrist axes of rotation according to the invention, and a sensor being advantageously present in the wrist - in such a manner that a sensitive detection of external forces/torques is possible about all of the three axes, and also a high degree of mobility is possible largely due entirely to the simple reconfiguration of the wrist. Both properties can be particularly well utilized for handling objects in a working space on and/or above, by way of example, a tabletop work surface.

An advantageous development of the robot wrist is characterized in that the robot wrist is designed in such a manner that a projection of the wrist axis of rotation $HR_{HGV,3}$ onto

a plane spanned by the wrist axes of rotation $HR_{HGV,1}$ and $HR_{HGV,2}$ forms an angle in the range from 50 to 130° with the wrist axis of rotation $HR_{HGV,2}$.

An advantageous development of the robot wrist is characterized in that the robot wrist is designed in such a manner that the wrist axes of rotation $HR_{HGV,1}$ and $HR_{HGV,2}$ form an angle of 90°, and/or the projection of the wrist axis of rotation $HR_{HGV,3}$ onto the plane spanned by the wrist axes of rotation $HR_{HGV,1}$ and $HR_{HGV,2}$ forms an angle of 90° with the wrist axis of rotation $HR_{HGV,2}$.

An advantageous development of the robot wrist is characterized in that the robot wrist is designed in such a manner that the wrist joint connections HGV_1 , HGV_2 , HGV_3 , the wrist links HGL_1 and HGL_2 , and the effector E mounted on the wrist joint connection HGV_3 are designed in such a manner that a movement of the wrist link HGL_2 and the effector E about the wrist axis of rotation $HR_{HGV,2}$ is possible without hindrance in all poses of the robot arm.

An advantageous development of the robot wrist is characterized in that the robot wrist is designed in such a manner that the wrist joint connection HGV_3 is designed for detecting a force or a torque about the wrist axis of rotation $HR_{HGV,3}$, and/or the wrist joint connection HGV_1 is designed for detecting a force or a torque about the wrist axis of rotation $HR_{HGV,1}$.

Advantages of the robot wrist and advantageous developments of the robot wrist result from a corresponding and analogous application of the statements made above in reference to the proposed robot arm.

Finally, the invention relates to a robot, having a robot arm as described above.

Further advantages, features and details will become apparent from the following description, in which - where appropriate, with reference to the drawings - at least one embodiment is described in detail. The same, similar and/or functionally identical parts are indicated by the same reference numerals.

BRIEF DESCRIPTION OF THE DRAWINGS

In the drawings,

- Fig. 1 shows a highly schematic structure of a robot arm according to the invention, with six degrees of freedom ($N = 6$),
- Fig. 2 shows a highly schematic structure of a robot wrist according to the invention, and
- Fig. 3 shows a representation of an embodiment of a robot wrist joint according to the invention, on a robot arm.

DETAILED DESCRIPTION OF THE PREFERRED EMBODIMENTS

Fig. 1 shows a highly schematic structure of a robot arm according to the invention, with six degrees of freedom. The robot arm has six actuator-drivable joint connections GV_n , which are connected in series via arm links GL_i , where $n = 1, 2, \dots, 6$, and $i = 1, 2, \dots, 5$. The proximal arm link GL_1 of the robot arm is connected via the joint connection GV_1 to a robot body RK . The distal arm link GL_5 of the robot arm is connected via the joint connection GV_6 to an effector E . The effector E can be arranged directly on the joint connection GV_6 or on an adapter connected to the joint connection GV_6 . Each of the joint connections GV_4, GV_5, GV_6 enables a movement about an axis of rotation $R_{GV,4}, R_{GV,5}, R_{GV,6}$ assigned to the same. The portion of the robot arm in the dashed-line box forms the robot wrist. The arm links GL_1, GL_2 and GL_3 have a greater longitudinal extent than the arm links GL_4, GL_5 and the effector E .

Fig. 2 shows a highly schematized structure of a robot wrist joint according to the invention, having three actuator-drivable wrist joint connections HGV_n , which are connected in series via two wrist links HGL_i , where $n = 1, 2, 3$ and $i = 1, 2$.

The proximal wrist link HGL_1 of the robot wrist is connected to a robot arm via the wrist joint connection HGV_1 . The distal wrist link HGL_2 of the robot wrist is connected to an effector E via the wrist joint connection HGV_3 . The wrist links HGL_2 and HGL_1 are

connected via the wrist joint connection HGV_2 . Each of the wrist joint connections HGV_1 , HGV_2 , HGV_3 enables a movement about a wrist axis of rotation $HR_{GV,1}$, $HR_{GV,2}$, $HR_{GV,3}$ assigned to the same, and thus a three-dimensional orientation of the effector E in space.

Fig. 3 shows an illustration of an embodiment of a robot wrist according to the invention, on a robot arm. The illustrated robot wrist comprises three actuator-drivable wrist joint connections HGV_1 , HGV_2 , and HGV_3 which are connected in series via two wrist links HGL_1 and HGL_2 . The proximal wrist link HGL_1 of the robot wrist is connected to a robot arm via the wrist joint connection HGV_1 . The distal wrist link HGL_2 of the robot wrist can be connected via the wrist joint connection HGV_3 to an effector E (not shown). The wrist links HGL_2 and HGL_1 are connected via the wrist joint connection HGV_2 . Each of the wrist joint connections HGV_1 , HGV_2 , HGV_3 enables a movement about a wrist axis of rotation $HR_{HGV,1}$, $HR_{HGV,2}$, $HR_{HGV,3}$ assigned to the same, and thus a three-dimensional orientation of the effector E in space.

The robot wrist is designed in such a manner that the wrist axes of rotation $HR_{HGV,1}$ and $HR_{HGV,2}$ intersect at an angle in the range of 90° , and the wrist axis of rotation $HR_{HGV,3}$ has, for any arbitrary configuration of the robot hand joint, a radially constant spacing D1 from the wrist axis of rotation $HR_{HGV,2}$. In addition, a sensor for detecting a force or a torque about the respective wrist axis of rotation $HR_{HGV,1}$, $HR_{HGV,2}$, $HR_{HGV,3}$ is present in all of the wrist joint connections HGV_1 , HGV_2 , and HGV_3 .

CLAIMS

1. A robot arm, having a number N of actuator-drivable joint connections GV_n , which are connected in series via arm links GL_i , where $n = 1, 2, \dots, N$, and $i = 1, 2, \dots, N-1$, and $N \geq 6$, wherein
 - a proximal arm link GL_1 of the robot arm can be connected to a robot body RK via the joint connection GV_1 ,
 - a distal arm link GL_{N-1} of the robot arm can be connected to an effector E via the joint connection GV_N ,
 - the arm links GL_{N-1} and GL_{N-2} are connected via the joint connection GV_{N-1} , and the arm links GL_{N-2} and GL_{N-3} are connected via the joint connection GV_{N-2} , and
 - each of the joint connections GV_N , GV_{N-1} , GV_{N-2} enables a movement about an axis of rotation $R_{GV,N}$, $R_{GV,N-1}$, $R_{GV,N-2}$ assigned to the same,
characterized in that the robot arm is designed in such a manner that
 - the axes of rotation $R_{GV,N-2}$ and $R_{GV,N-1}$ intersect at an angle in the range from 50 to 130° ,
 - the axis of rotation $R_{GV,N}$ is arranged radially at a constant spacing $D1$ from the axis of rotation $R_{GV,N-1}$, and
 - the joint connection GV_{N-1} is adapted for detecting a force or torque about the axis of rotation $R_{GV,N-1}$; andcharacterised in that the constant spacing $D1$ is selected to be in the range from 1 to 50 cm.
2. The robot arm according to claim 1, **characterized in that** the robot arm is designed in such a manner that a projection of the axis of rotation $R_{GV,N}$ onto a plane spanned by the axes of rotation $R_{GV,N-2}$ and $R_{GV,N-1}$ forms an angle in the range from 50 to 130° with the axis of rotation $R_{GV,N-1}$.
3. The robot arm according to claim 2, **characterized in that** the axes of rotation $R_{GV,N-2}$ and $R_{GV,N-1}$ form an angle of 90° , and/or the projection of the axis of rotation $R_{GV,N}$ onto the plane spanned by the axes of rotation $R_{GV,N-2}$ and $R_{GV,N-1}$ forms an angle of 90° with the axis of rotation $R_{GV,N-1}$.

4. The robot arm according to any one of the claims 1 to 3,
characterized in that the joint connection GV_N is adapted for detecting a force or a torque about the axis of rotation $R_{GV,N}$, and/or the joint connection GV_{N-2} is adapted for detecting a force or a torque about the axis of rotation $R_{GV,N-2}$.

5. The robot arm according to any one of the claims 1 to 4,
characterized in that the robot arm is designed in such a manner that
 - the axes of rotation R_{GV1} and R_{GV2} intersect at an angle in the range from 50 to 130°,
 - the axes of rotation R_{GV2} and R_{GV3} intersect at an angle in the range from 50 to 130°,
 - the axis of rotation R_{GV4} is arranged radially at the constant spacing $D1$ from the axis of rotation R_{GV3} , and
 - the axes of rotation R_{GV4} and R_{GV5} intersect at an angle in the range from 50 to 130°.

6. The robot arm according to any one of the claims 1 to 4,
characterized in that the robot arm is designed in such a manner that
 - the axes of rotation R_{GV1} and R_{GV2} intersect at an angle in the range from 50 to 130°,
 - the axes of rotation R_{GV2} and R_{GV3} intersect at an angle in the range from 50 to 130°,
 - the axes of rotation R_{GV3} and R_{GV4} intersect at an angle in the range from 50 to 130°,
 - the axis of rotation R_{GV5} is arranged radially at the constant spacing $D1$ from the axis of rotation R_{GV4} .

7. The robot arm according to any one of the claims 1 to 4,
characterized in that the robot arm is designed in such a manner that
 - the axes of rotation R_{GV1} and R_{GV2} intersect at an angle in the range from 50 to 130°,
 - the axes of rotation R_{GV2} and R_{GV3} intersect at an angle in the range from 50

to 130° ,

- the axis of rotation R_{GV4} is arranged radially at the constant spacing D1 from the axis of rotation R_{GV3} , and
- the axis of rotation R_{GV5} is arranged radially at the constant spacing D1 from the axis of rotation R_{GV4} .

8. A robot wrist, having three actuator-drivable wrist joint connections HGV_n , which are connected in series via two wrist links HGL_i , where $n = 1, 2$, or 3 and $i = 1$ or 2 , wherein

- a proximal wrist link HGL_1 of the robot wrist can be connected to a robot arm via the wrist joint connection HGV_1 ,
- a distal wrist link HGL_2 of the robot wrist can be connected to an effector E via the wrist joint connection HGV_3 ,
- the wrist links HGL_2 and HGL_1 are connected via the wrist joint connection HGV_2 , and
- each of the wrist joint connections HGV_1 , HGV_2 , HGV_3 enables a movement about a wrist axis of rotation $HR_{HGV,1}$, $HR_{HGV,2}$, $HR_{HGV,3}$ assigned to the same, **characterized in that** the robot wrist is designed in such a manner that
- the wrist axes of rotation $HR_{HGV,1}$ and $HR_{HGV,2}$ intersect at an angle in the range from 50 to 130° ,
- the wrist axis of rotation $HR_{HGV,3}$ is arranged radially at a constant spacing D1 from the wrist axis of rotation $HR_{HGV,2}$, and
- the wrist joint connection HGV_2 is designed for detecting a force or a torque about the wrist axis of rotation $HR_{HGV,2}$.

9. The robot wrist according to claim 8,

characterized in that the robot wrist is designed in such a manner that a projection of the wrist axis of rotation $HR_{HGV,3}$ onto a plane spanned by the wrist axes of rotation $HR_{HGV,1}$ and $HR_{HGV,2}$ forms an angle in the range from 50 to 130° with the wrist axis of rotation $HR_{HGV,2}$.

10. Robot wrist according to claim 9,

characterized in that the wrist axes of rotation $HR_{HGV,1}$ and $HR_{HGV,2}$ form an angle of 90° , and/or the projection of the wrist axis of rotation $HR_{HGV,3}$ onto the

plane spanned by the wrist axes of rotation $HR_{HGV,1}$ and $HR_{HGV,2}$ forms an angle of 90° with the wrist axis of rotation $HR_{HGV,2}$.

11. Robot wrist according to any one of the claims 8 to 10,
characterized in that the wrist joint connection HGV_3 is designed for detecting a force or a torque about the wrist axis of rotation $HR_{HGV,3}$, and/or the wrist joint connection HGV_1 is designed for detecting a force or a torque about the wrist axis of rotation $HR_{HGV,1}$.
12. A robot, having a robot arm according to any one of the claims 1 to 7, or a robot wrist according to any one of the claims 8 to 11.