# Article information:

Human-Like Behavior Generation Based on Head-Arms Model for Robot Tracking External Targets and Body Parts | IEEE Journals & Magazine | IEEE Xplore  
<https://ieeexplore.ieee.org/document/6902763>

# Article summary:

1. This paper proposes a scheme to generate coordinated head-arm motion for a humanoid robot with two degrees-of-freedom for the head and seven for each arm.

2. A virtual plane approach is employed to generate the analytical solution of the head motion, while a quadratic program (QP)-based method is used to formulate the coordinated dual-arm motion.

3. The effectiveness of the proposed scheme is demonstrated using both computer simulation and physical experiments.

# Article rating:

May be slightly imbalanced: The article presents the information in a generally reliable way, but there are minor points of consideration that could be explored further or claims that are not fully backed by appropriate evidence. Some perspectives may also be omitted, and you are encouraged to use the research topics section to explore the topic further.

# Article analysis:

The article provides an overview of a proposed scheme to generate coordinated head-arm motion for a humanoid robot with two degrees-of-freedom for the head and seven for each arm. The article is well written and provides clear explanations of the proposed methods, as well as results from computer simulations and physical experiments that demonstrate its effectiveness.

The article does not appear to be biased or one-sided in its reporting, as it presents both sides of the argument equally. It also does not contain any unsupported claims or missing points of consideration, as all claims are supported by evidence from computer simulations and physical experiments. Furthermore, there is no promotional content or partiality in the article, as it focuses solely on presenting research findings without any attempt to promote any particular product or service.

The article does note possible risks associated with using robots in social settings, such as potential safety issues if robots are not properly programmed or monitored. However, it does not explore counterarguments or present both sides equally when discussing these risks; instead, it focuses mainly on presenting research findings related to generating human-like behavior in robots rather than exploring potential risks associated with their use in social settings.

# Topics for further research:

* Humanoid robot safety
* Human-robot interaction
* Humanoid robot motion control
* Humanoid robot coordination
* Humanoid robot social interaction
* Humanoid robot ethical considerations

# Report location:

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