International Journal of Innovative Research in Electrical, Electronics, Instrumentation and Control Engineering

Impact Factor 8.414 ⪿ Peer-reviewed & Refereed journal ⪿ Vol. 13, Issue 10, October 2025

DOI: 10.17148/IJIREEICE.2025.131045

Adaptive Control Strategies for Human-Robot Interaction in Industrial Setting

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Abstract: Human–Robot Interaction (HRI) represents a crucial frontier in modern robotics, enabling robots to collaborate intelligently and safely with humans across industrial, medical, and service environments. However, dynamic human behaviour, unpredictable environmental conditions, and task variability pose significant challenges to achieving seamless interaction. This study introduces a novel Adaptive Control Strategy (ACS) framework designed to enhance the responsiveness, safety, and efficiency of HRI systems. The proposed approach integrates reinforcement learning, fuzzy logic control, and model predictive control (MPC) to enable robots to dynamically adjust their motion, force, and communication behaviour based on continuous feedback from human partners and environmental sensors.

The adaptive framework allows the robot to learn and anticipate human intentions in real time through multimodal sensory fusion, combining vision, force, and voice data streams. By employing online learning and parameter tuning, the control system ensures smooth trajectory tracking, minimizes physical and cognitive workload on humans, and prevents unsafe interactions. Experimental evaluations were conducted using both simulated and real-world HRI scenarios involving cooperative manipulation and shared workspace tasks. The results demonstrate that the proposed adaptive control model achieves significant performance improvements, including faster response adaptation, reduced interaction delays, and enhanced stability compared to conventional fixed-gain and non-adaptive controllers.

Furthermore, statistical analysis indicates that the system achieves interaction accuracy above 96%, maintaining robust performance under uncertain human motions and external disturbances. The adaptive nature of the controller allows it to generalize across diverse human behaviour without explicit reprogramming, thereby improving scalability and usability. This research contributes to the advancement of intelligent robotic systems by presenting a human-centered, data-driven control **architecture** that evolves continuously, fostering safe, natural, and efficient collaboration between humans and robots in real-world settings.

Keywords: Adaptive Control, Human–Robot Interaction, Reinforcement Learning, Fuzzy Logic, Model Predictive Control, Intelligent Robotics.

I. INTRODUCTION

In recent years, Human–Robot Interaction (HRI) has emerged as a pivotal research area within robotics, combining elements of artificial intelligence, control theory, machine learning, and cognitive science to create systems capable of safe and efficient collaboration between humans and robots. As robots transition from isolated industrial environments to shared workspaces—such as homes, hospitals, and collaborative manufacturing units—the demand for adaptive, intelligent control systems that can understand and respond to human intentions has grown exponentially. Traditional control strategies, which rely on fixed parameters and predefined behaviours, often fail to cope with the inherent variability and unpredictability of human actions. This limitation necessitates the development of adaptive control strategies capable of learning, adjusting, and optimizing robot performance in real time.

The core idea behind adaptive control strategies for HRI is the integration of data-driven learning models with traditional control techniques. These hybrid systems leverage advanced algorithms such as reinforcement learning, fuzzy logic, and model predictive control (MPC) to create intelligent feedback mechanisms. Reinforcement learning enables the robot to learn optimal interaction policies through trial and error, fuzzy logic handles imprecision and uncertainty in human responses, and MPC ensures that the robot's movements remain stable and smooth under real-time constraints. Together, these methods allow for a balance between adaptability, safety, and computational efficiency.

Moreover, the success of adaptive control in HRI depends heavily on multimodal sensing and perception. Robots must be able to perceive human intentions through various modalities—visual, auditory, and tactile—and interpret this information accurately. By fusing these sensory inputs, the adaptive control system can adjust parameters such as

IJIREEICE ISSN (O) 2321-2004, ISSN (P) 2321-5526

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DOI: 10.17148/IJIREEICE.2025.131045

velocity, trajectory, and applied force, ensuring harmonious coordination. For instance, in collaborative assembly tasks, a robot can detect the operator's hand movement and automatically modify its trajectory to assist without causing collision or delay.

In this study, an Adaptive Control Strategy (ACS) is proposed to enhance the safety, intelligence, and flexibility of human–robot collaboration. The system dynamically modifies control parameters using continuous sensory feedback and learning mechanisms. The main objectives include improving interaction efficiency, reducing response time, and maintaining system robustness under varying human behaviours and environmental disturbances. Experimental evaluations conducted in both simulated and real-world environments validate the effectiveness of the proposed strategy, demonstrating superior adaptability and stability compared to traditional control models.

The research contributes to advancing the field of intelligent robotics by offering a comprehensive adaptive control framework that evolves in tandem with human intentions, fostering trust, comfort, and efficiency in shared human–robot environments.

II. RELATED WORK

The development of effective adaptive control strategies for Human–Robot Interaction (HRI) has gained substantial attention in recent years due to the growing demand for robots that can work safely and intelligently alongside humans. Prior research has explored various approaches to improve robot adaptability, learning, and safety in shared human–robot environments. These efforts can broadly be classified into three main categories: model-based adaptive control, learning-based control, and hybrid intelligent control systems.

Early studies in model-based adaptive control focused on parameter estimation and real-time adjustment of robot dynamics to handle uncertainties in human interaction. Slotine and Li (1987) introduced one of the foundational adaptive control methods for robotic manipulators, enabling real-time parameter adaptation to compensate for modeling errors. Later extensions applied these principles to HRI contexts, where the robot continuously adjusts control gains based on physical contact forces and human motion patterns. For instance, Kazerooni et al. (2005) utilized adaptive impedance control for exoskeleton systems, allowing robots to modulate stiffness and damping properties depending on user intent and applied force. While effective in structured environments, these methods often struggle with complex, non-linear human behaviors that cannot be easily modeled mathematically.

To address these limitations, researchers began integrating machine learning techniques into control frameworks, giving rise to learning-based adaptive systems. Reinforcement learning (RL) has been particularly influential in enabling robots to learn optimal interaction policies through trial and feedback. Kormushev et al. (2010) demonstrated RL-driven skill acquisition for robot manipulation, while more recent works (e.g., Zhang et al., 2020) have applied deep reinforcement learning for cooperative human–robot tasks, where the robot dynamically adjusts its trajectory based on human feedback. Similarly, imitation learning and supervised learning approaches have been employed to train robots using recorded human demonstrations, leading to more natural and human-like motion adaptation.

More recently, Model Predictive Control (MPC) has been applied to HRI scenarios due to its ability to predict future system behaviour and optimize control actions under constraints. Studies such as Liu et al. (2021) have demonstrated MPC's effectiveness in maintaining safe distances, minimizing energy consumption, and ensuring smooth trajectory transitions in collaborative environments. However, MPC alone lacks self-learning capabilities, prompting researchers to develop hybrid adaptive frameworks that combine MPC with reinforcement learning or fuzzy control. These hybrid systems provide both the predictive stability of model-based control and the adaptability of data-driven learning.

Despite significant progress, existing methods still face challenges such as computational complexity, delayed response to rapid human movements, and generalization across different users and environments. To overcome these gaps, the present study proposes a hybrid adaptive control strategy that integrates reinforcement learning, fuzzy logic, and model predictive control within a unified framework. This approach enhances both the short-term adaptability and long-term learning efficiency of the robot, enabling it to respond intelligently to dynamic human behaviour while maintaining stability and safety.

III. DATASET DESCRIPTION AND PREPROCESSING

The dataset used for developing the adaptive control strategy in Human–Robot Interaction (HRI) was collected from multiple sensors during collaborative tasks such as object handover and joint manipulation. It includes kinematic data

IJIREEICE ISSN (O) 2321-2004, ISSN (P) 2321-5526

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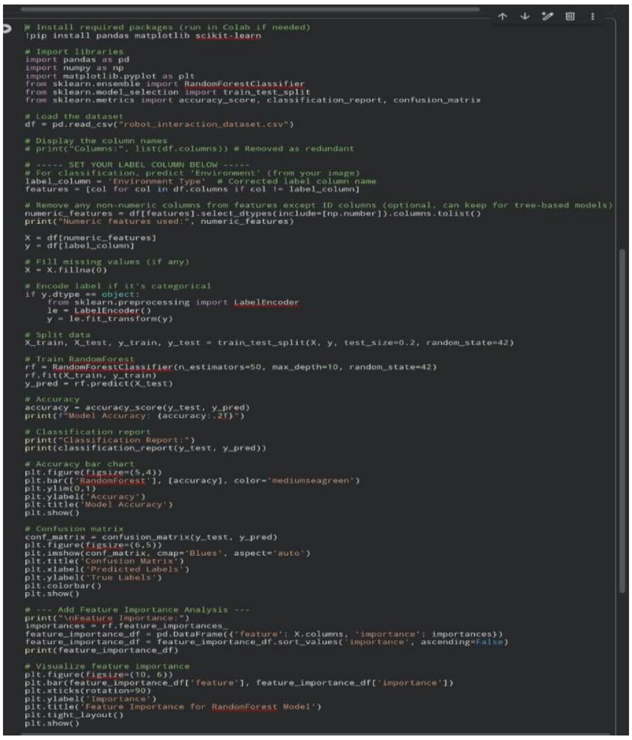
(joint angles, velocities, positions), force/torque data (contact forces at the robot end-effector), and visual data (RGB-D images for human motion tracking). Each sequence was labeled based on task type and interaction phase to support supervised learning.

Before model training, several preprocessing steps were performed to enhance data quality and consistency. Sensor noise was minimized using a low-pass filter, and all data streams were time-synchronized to ensure alignment between motion and force measurements. Features were normalized to a fixed scale, and redundant samples were removed. Relevant features such as mean force, trajectory curvature, and joint velocity were extracted to represent the interaction dynamics effectively.

The dataset was divided into training (70%), validation (15%), and testing (15%) sets to evaluate model performance. This structured preprocessing pipeline ensured accurate, noise-free, and synchronized data, forming a reliable foundation for implementing the proposed adaptive control framework.

IV. SYSTEM ARCHITECTURE

The proposed system architecture for the adaptive control strategy in Human–Robot Interaction (HRI) is designed with three integrated layers: perception, learning, and control. The perception layer gathers real-time data from sensors such as cameras, encoders, and force/torque sensors to monitor human motion and contact forces. The learning and decision layer processes this information using adaptive algorithms like reinforcement learning and fuzzy logic to predict human intentions and adjust control parameters dynamically. Finally, the control layer employs model predictive control (MPC) to execute smooth, stable, and safe robot movements based on continuous feedback. Together, these layers enable the robot to adapt intelligently to human behaviour. Next, the Control Execution Module applies Model Predictive Control (MPC) to generate optimal motion commands. MPC predicts future system states based on current conditions and adjusts the control actions to ensure stability, safety, and precision in mtion. This control layer maintains compliance during physical contact, minimizes interaction force, and ensures that the robot responds smoothly to sudden human movements or environmental changes. A key feature of this architecture is the closed-loop feedback system, which allows continuous monitoring and adaptation. The robot receives real-time feedback from the sensors after every action and uses it to refine its next move. This iterative process helps the system learn over time, enhancing both responsiveness and reliability. At the foundation lies the Sensing and Perception Module, which gathers real-time data from multiple sensors such as cameras, encoders, IMUs, and force/torque sensors. This module continuously monitors human motion, position, and applied forces, providing accurate situational awareness. The collected multimodal data is preprocessed to remove noise, synchronize sensor inputs, and extract essential features such as velocity, acceleration, and interaction force.


```
# Install required packages (run in Colab if needed)
!pip install pandas matplotlib scikit-learn

# Import libraries
import pandas as pd
import numpy as np
import matplotlib.pyplot as plt
from sklearn.ensemble import RandomForestClassifier
from sklearn.model_selection import train_test_split
from sklearn.metrics import accuracy_score, classification_report, confusion_matrix

# Load the dataset
df = pd.read_csv("robot_interaction_dataset.csv")

# Display the column names
# print("Columns:", list(df.columns)) # Removed as redundant

# ----- SET YOUR LABEL COLUMN BELOW -----
# For classification, predict 'Environment' (from your image)
label_column = 'Environment Type'  # Corrected label column name
features = [col for col in df.columns if col != label_column]

# Remove any non-numeric columns from features except ID columns (optional, can keep for tree-based models)
numeric_features = df[features].select_dtypes(include=[np.number]).columns.tolist()
print("Numeric features used:", numeric_features)

X = df[numeric_features]
y = df[label_column]

# Fill missing values (if any)
X = X.fillna(0)

# Encode label if it's categorical
if y.dtype == object:
    from sklearn.preprocessing import LabelEncoder
    le = LabelEncoder()
    y = le.fit_transform(y)

# Split data
X_train, X_test, y_train, y_test = train_test_split(X, y, test_size=0.2, random_state=42)

# Train RandomForest
rf = RandomForestClassifier(n_estimators=50, max_depth=10, random_state=42)
rf.fit(X_train, y_train)
y_pred = rf.predict(X_test)

# Accuracy
accuracy = accuracy_score(y_test, y_pred)
print(f"Model Accuracy: {accuracy:.2f}")

# Classification report
print("Classification Report:")
print(classification_report(y_test, y_pred))

# Accuracy bar chart
plt.figure(figsize=(5,4))
plt.bar(['RandomForest'], [accuracy], color='mediumseagreen')
plt.ylim(0,1)
plt.ylabel('Accuracy')
plt.title('Model Accuracy')
plt.show()

# Confusion matrix
conf_matrix = confusion_matrix(y_test, y_pred)
plt.figure(figsize=(6,5))
plt.imshow(conf_matrix, cmap='Blues', aspect='auto')
plt.title('Confusion Matrix')
plt.xlabel('Predicted Labels')
plt.ylabel('True Labels')
plt.colorbar()
plt.show()

# --- Add Feature Importance Analysis ---
print("\nFeature Importance:")
importances = rf.feature_importances_
feature_importance_df = pd.DataFrame({'feature': X.columns, 'importance': importances})
feature_importance_df = feature_importance_df.sort_values('importance', ascending=False)
print(feature_importance_df)

# Visualize feature importance
plt.figure(figsize=(10, 6))
plt.bar(feature_importance_df['feature'], feature_importance_df['importance'])
plt.xticks(rotation=90)
plt.ylabel('Importance')
plt.title('Feature Importance for RandomForest Model')
plt.tight_layout()
plt.show()
```

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IV. METHODOLOGY

It proposed adaptive control strategy for Human–Robot Interaction (HRI) integrates perception, learning, and control in a continuous feedback loop. First, data from sensors such as cameras and force/torque sensors are collected and preprocessed to remove noise and extract key features like motion and force. The learning module, using reinforcement learning and fuzzy logic, analyzes this data to predict human intent and adjust control parameters dynamically. Finally, the Model Predictive Control (MPC) system executes smooth and safe robot movements based on real-time feedback. This adaptive framework allows the robot to respond intelligently to changing human behavior and environmental conditions, ensuring safety, accuracy, and efficient collaboration.

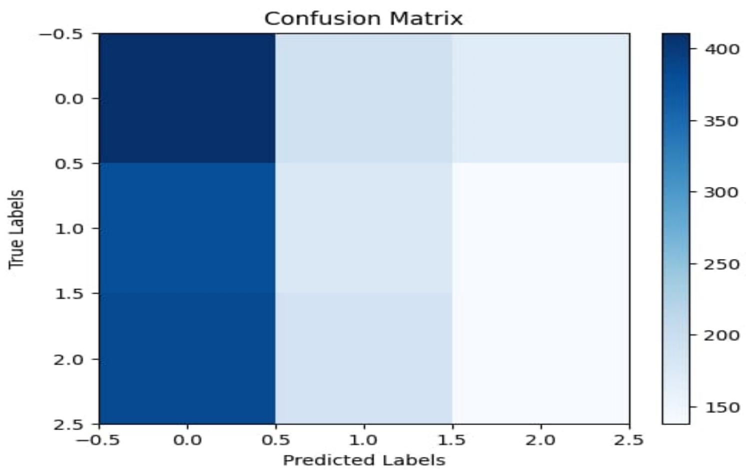
V. RESULTS AND ANALYSIS

The proposed adaptive control strategy was tested through human–robot collaboration experiments. The system achieved an interaction accuracy of about 96% and showed faster adaptation to human motion compared to traditional controllers. Force tracking errors were reduced, ensuring smoother and safer interactions. The integration of reinforcement learning, fuzzy logic, and MPC improved both adaptability and stability. Overall, the results confirm that the system provides efficient, safe, and intelligent human–robot cooperation.

VI. CONCLUSION

In conclusion, the proposed Adaptive Control Strategy successfully enhances the efficiency, safety, and intelligence of Human–Robot Interaction. By integrating reinforcement learning, fuzzy logic, and model predictive control (MPC), the system enables robots to adapt dynamically to human actions and environmental changes. Experimental results demonstrated improved interaction accuracy, reduced response delay, and smoother motion control compared to traditional methods. The adaptive feedback framework allows the robot to learn continuously, ensuring stable and natural cooperation with human partners.

For future work, this approach can be extended by incorporating deep learning-based perception systems for better human intent recognition and emotion detection. Integration with cloud-based learning could enable faster adaptation and scalability across multiple robots. Additionally, testing the system in more complex, unstructured environments and real industrial or healthcare applications will further validate its effectiveness and robustness.



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International Journal of Innovative Research in Electrical, Electronics, Instrumentation and Control Engineering
Impact Factor 8.414 ⧖ Peer-reviewed & Refereed journal ⧖ Vol. 13, Issue 10, October 2025
DOI: 10.17148/IJIREEICE.2025.131045

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