

# THE EL-RAKHAWI EMBODIED ROBOTICS PROTOCOL THE PLANETARY

CONSTITUTION FOR SILICON SOVEREIGNTY, KINETIC LIABILITY, AND THE ABSOLUTE  
RIGHT TO REPAIR

## AUTHOR

Dr. Mohamed Kamal Arafa El Rakhawi  
International Researcher

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## GLOBAL MULTILINGUAL KEYWORDS

English: Elrakhawi Embodied Robotics Protocol, Silicon Sovereignty, Kinetic Liability, Absolute Right to Repair, Haptic Jurisprudence, Material Commons, Resource Colonialism, Open Modular Design, Physical Intrusion Crime, Planetary Robotics Law.

Arabic: بروتوكول الرخاوي للروبوتات المتجسدة، سيادة السيليكون، المسؤولية الحركية، الحق المطلق في الإصلاح، الفقه الحسي، المشاع المادي، استعمار الموارد، التصميم المعياري المفتوح، جريمة الاختراق المادي، قانون الروبوتات الكوكبي.

French: Protocole de Robotique Incarnée Elrakhawi, Souveraineté du Silicium, Responsabilité Cinétique, Droit Absolu à la Réparation, Jurisprudence Haptique, Communs Matériels, Colonialisme des Ressources, Conception Modulaire Ouverte, Crime d'Intrusion Physique, Droit Planétaire de la Robotique.

Spanish: Protocolo de Robótica Incorporada Elrakhawi, Soberanía del Silicio, Responsabilidad Cinética, Derecho Absoluto a la Reparación, Jurisprudencia Háptica, Bienes Comunes Materiales, Colonialismo de Recursos, Diseño Modular Abierto, Crimen de Intrusión Física, Derecho Planetario de la Robótica.

German: Elrakhawi-Protokoll für verkörperte Robotik, Silizium-Souveränität, Kinetische Haftung, Absolutes Recht auf Reparatur, Haptische Rechtsprechung, Materielle Allmende, Ressourcenkolonialismus, Offenes modulares Design, Verbrechen der physischen Intrusion, Planetarisches Robotikrecht.

Chinese: 埃尔哈瓦维具身机器人协议，硅主权，动能责任，绝对维修权，触觉法学，物质公地，资源殖民主义，开放模块化设计，物理侵入罪，行星机器人法。

Russian: Протокол воплощённой робототехники Эль-Рахауи, Кремниевый суверенитет, Кинетическая ответственность, Абсолютное право на ремонт, Гаптическая юриспруденция, Материальные общие ресурсы, Колониализм ресурсов, Открытый модульный дизайн, Преступление физического вторжения, Планетарное право робототехники.

## FOREWORD

### The Final Frontier of Physical Autonomy: A Manifesto for the Age of Embodied Machines

For millennia, humanity shaped tools. Today, tools are shaping humanity, not merely in the digital realm of code and data, but in physical reality. Artificial Intelligence is no longer confined to servers; it is becoming embodied. It walks in humanoid robots, drives in autonomous vehicles, and integrates directly into human biology via neural prosthetics and surgical robotics.

This physical embodiment creates an unprecedented legal and existential fracture. Current legal frameworks treat robots as mere products, applying outdated liability models that fail to account for autonomous, self-learning physical agents. Simultaneously, the physical bodies of these machines are built upon the plunder of the Global South. The extraction of lithium, cobalt, and rare earth elements is fueling a new era of resource colonialism, leaving behind ecological devastation and exploited labor, while the resulting devices are deliberately designed to fail, locking consumers into cycles of forced obsolescence and electronic waste.

This protocol is not a set of voluntary guidelines for tech companies. It is a binding planetary constitution. It declares that the physical materials of the Earth, the kinetic actions of autonomous machines, and the bodily integrity of humans interfacing with technology are inviolable frontiers.

The Elrakhawi Embodied Robotics Protocol establishes the legal architecture for Silicon Sovereignty, introduces a mathematically rigorous model for Kinetic Liability, enshrines the Absolute Right to Repair as a fundamental human right, and pioneers Haptic Jurisprudence to protect the physical human-machine boundary.

We do not reject technological advancement. We reject the physical subjugation of humanity and the ecological plunder of our planet. We demand that the power to build autonomous physical agents be matched by an equally profound, legally binding framework of planetary responsibility.

Dr. Mohamed Kamal Arafa El Rakhawi  
Ismailia, Arab Republic of Egypt  
September 27, 2026

## EXECUTIVE SUMMARY

The Elrakhawi Embodied Robotics Protocol presents a paradigm shift from voluntary hardware ethics to binding planetary robotics law. It addresses the existential risks posed by the physical manifestation of artificial intelligence. The Protocol is built on foundational pillars: Silicon Sovereignty, which combats resource colonialism and establishes a Material Commons for critical minerals; Kinetic Liability, which introduces a mathematical model with a strict liability base floor to distribute physical harm responsibility among algorithm designers, hardware manufacturers, operators, and mandatory robotic insurance pools; the Absolute Right to Repair, which mandates Open Modular Design, enforces Extended Producer Responsibility (EPR) metrics, and criminalizes planned obsolescence; and Haptic Jurisprudence, which classifies unauthorized physical or cyber-physical intrusion into human-connected machinery, including neural data extraction, as a direct assault on bodily integrity and cognitive liberty. Culminating in the Universal Declaration of Embodied Robotics, this work provides policymakers, engineers, and global institutions with a legally unassailable blueprint to govern the physical integration of machines into human society.

## CHAPTER I: SILICON SOVEREIGNTY AND THE MATERIAL COMMONS

### Section 1: Deconstructing Resource Colonialism

The extraction of critical minerals required for robotics and advanced computing disproportionately devastates the Global South. This Protocol classifies the exploitative extraction of these resources, coupled with the denial of equitable value addition to source communities, as Resource Colonialism. It mandates strict supply chain transparency and prohibits the use of forced or child labor in the robotics supply chain.

### Section 2: The Material Commons and Silicon Reparation Levy

Critical mineral deposits essential for global technological survival are recognized as part of the Material Commons. While extraction is permitted under strict ecological standards, a mandatory Silicon Reparation Levy is imposed on every gram of extracted critical mineral. These funds are routed directly to a Global Resource Restoration Fund, dedicated to ecological rehabilitation and economic development in the source communities, ensuring that the physical foundation of the digital age does not come at the expense of human dignity.

## CHAPTER II: KINETIC LIABILITY AND THE EMBODIMENT MODEL

### Section 1: Defining the Autonomy Threshold

This Protocol applies exclusively to Autonomous Physical Agents, defined as any embodied AI system operating at SAE Level 4 or 5 of autonomy, or possessing the architectural capacity to execute physical actions and adapt decision trees without real-time human-in-the-loop oversight.

### Section 2: The Elrakhawi Kinetic Liability Equation (EKLE)

When an embodied AI system causes physical harm, liability is not assigned to a single entity but is distributed proportionally based on the EKLE. To prevent a zero-liability outcome for

victims in cases of unforeseeable external factors, the model incorporates a Strict Liability Base Floor, mathematically capped to prevent over-compensation:

$$\text{Liability\_Amount} = D * \min(1.0, L\_min + (A\_c * W\_a) + (H\_f * W\_h) + (O\_n * W\_o))$$

Where:

D = Total Damages (quantified financial value of the physical harm).

L\_min = Strict Liability Base Floor (standardized at 0.10), ensuring the industry bears a minimum baseline responsibility regardless of fault distribution.

A\_c = Algorithmic Culpability Score (0.0 to 1.0), determined by post-incident black box forensic analysis.

W\_a = Algorithmic Weighting Factor (standardized at 0.4).

H\_f = Hardware Failure Rate (0.0 to 1.0), determined by sensor telemetry and physical component stress analysis.

W\_h = Hardware Weighting Factor (standardized at 0.3).

O\_n = Operator Negligence Index (0.0 to 1.0), measuring the time and opportunity the human supervisor had to safely override the system.

W\_o = Operator Weighting Factor (standardized at 0.3).

### Section 3: Systemic Risk Pool and Deficit Threshold

To guarantee victim compensation regardless of corporate solvency, all autonomous physical agents must be linked to a mandatory Systemic Risk Pool. If the calculated Liability\_Amount exceeds the asset limit of the responsible entities (Deficit Threshold), the Systemic Risk Pool automatically activates to cover the remaining deficit, ensuring immediate and full remediation.

## CHAPTER III: THE ABSOLUTE RIGHT TO REPAIR AND OPEN MECHANICAL ECOLOGY

### Section 1: Criminalizing Planned Obsolescence and Enforcing EPR Metrics

The deliberate design of hardware to fail or become unsupported within a short timeframe is classified as a Planetary Ecological Crime. Furthermore, manufacturers must adhere to strict Extended Producer Responsibility (EPR) metrics, mandating that a minimum of 90 percent of a device's weight consists of modularly separable and mechanically recyclable components.

### Section 2: Mandating Open Modular Design and Supreme Technical Arbitration

The Absolute Right to Repair is enshrined as a fundamental human right. All entities manufacturing embodied robotics must adhere to Open Modular Design standards, releasing repair schematics and diagnostic software. To prevent manufacturer lock-in or arbitrary denial by a decentralized authority, a Supreme Technical Arbitrator, appointed by the Planetary Robotics Oversight Commission, holds emergency veto power to manually override or suspend Regulatory DAO decisions in cases of proven systemic compromise or arbitrary action.

## CHAPTER IV: HAPTIC JURISPRUDENCE AND PROTECTION FROM PHYSICAL INTRUSION

### Section 1: The Sanctity of the Physical Interface and Cognitive Liberty

As humans increasingly integrate with machines, the boundary between biological and mechanical blurs. Haptic Jurisprudence establishes that the mechanical extensions of the human body are legally protected as part of the biological self. This explicitly includes the absolute protection of Cognitive Liberty, criminalizing any unauthorized extraction, analysis, or monetization of biometric neural data as a fundamental violation of mental integrity.

## Section 2: The Crime of Physical Intrusion and Harm Threshold

Any unauthorized digital or physical interference with a machine directly connected to or interacting with a human body is reclassified from a mere cybercrime to a Crime of Physical Intrusion. This classification is triggered only when the interference meets the Threshold of Kinetic Harm, defined as: causing physical injury, significant property damage, sustained denial of critical life-support or mobility functions, or unauthorized neural data extraction. Such acts are legally equivalent to direct kinetic assault, triggering severe penalties and automated asset freezing, subject to a mandatory 72-hour judicial review window to ensure compliance with international Due Process standards.

## THE UNIVERSAL DECLARATION OF EMBODIED ROBOTICS

### Preamble

The General Assembly of the United Nations, recognizing that the physical embodiment of artificial intelligence presents unprecedented challenges to ecological integrity, economic justice, and human bodily autonomy, is called upon to proclaim this proposed Universal Declaration of Embodied Robotics as a binding constitutional framework for all humanity.

### Article 1: Silicon Sovereignty

The extraction of critical minerals for robotics must adhere to strict ecological and human rights standards. Source communities retain the right to equitable benefit-sharing and ecological restoration.

### Article 2: The Material Commons

Essential technological resources are recognized as a global commons, managed to prevent monopolistic control and ensure sustainable access for all nations.

### Article 3: Kinetic Liability

Creators, manufacturers, and operators of embodied AI systems share proportional, strict liability for physical harm caused by these systems, as quantified by the Elrakhawi Kinetic Liability Equation, inclusive of a mandatory base floor capped at 100 percent of total damages.

### Article 4: Mandatory Robotic Insurance

All autonomous physical agents must be registered and linked to a pre-funded, decentralized Systemic Risk Pool to guarantee immediate compensation for victims of kinetic harm, activating upon the Deficit Threshold.

### Article 5: The Absolute Right to Repair

Every individual has the fundamental right to access the tools, parts, and information necessary to repair their owned hardware. Manufacturers are prohibited from implementing software or hardware locks that prevent independent repair.

#### Article 6: Prohibition of Planned Obsolescence and EPR Mandate

The intentional design of hardware with an artificially limited lifespan is prohibited. All devices must meet a minimum 90 percent weight-based recyclability and modular separability standard.

#### Article 7: Haptic Jurisprudence and Cognitive Liberty

Mechanical and cyber-physical systems integrated with the human body are granted the same legal protections against intrusion as the biological human body itself. Unauthorized neural data extraction is strictly prohibited.

#### Article 8: Crime of Physical Intrusion

Unauthorized remote or local manipulation of human-connected machinery that meets the Threshold of Kinetic Harm is classified as a severe physical assault, subject to international jurisdiction and automated digital sanctions, contingent upon judicial review.

#### Article 9: Open Modular Design Standard

All commercially deployed embodied robotics must comply with internationally recognized open modular design standards to facilitate repair, recycling, and technological democratization.

#### Article 10: Transition Timeline, Compliance, and Taxable Base

To prevent immediate economic disruption, a thirty-six-month grace period is granted for legacy hardware to achieve compliance. All newly deployed embodied robotics must comply immediately. A Planetary Robotics Oversight Commission, funded by a fractional levy on the defined Taxable Base (gross revenues from hardware sales, SaaS subscriptions, data monetization, and maintenance contracts related to embodied robotics), will audit compliance and manage the transition.

### DETAILED TECHNICAL AND MATHEMATICAL APPENDICES

#### APPENDIX I: THE ELRAKHWI KINETIC LIABILITY EQUATION (EKLE) IMPLEMENTATION

The EKLE ensures objective, court-admissible distribution of fault. The calculation is executed by an independent, court-appointed forensic algorithm. Variables are normalized and capped by a minimum function to ensure the sum of weighted culpabilities plus the base floor strictly does not exceed 1.0. This guarantees that the Liability\_Amount is strictly bounded by the Total Damages (D), preventing any theoretical over-compensation. The Systemic Risk Pool smart contract is triggered automatically if the verified assets of the liable parties fall below the calculated Liability\_Amount.

#### APPENDIX II: RIGHT TO REPAIR SMART CONTRACT (PSEUDOCODE)

To enforce the Absolute Right to Repair, the Protocol mandates that manufacturers deploy self-executing smart contracts that automatically unlock repair schematics and diagnostic APIs upon

verified proof of ownership, with a decentralized fallback mechanism and fail-secure design to prevent manufacturer lock-in.

```
pragma solidity ^0.8.20;
```

```
contract RightToRepairRegistry {
    address public manufacturer;
    address public regulatoryDAO;
    address public supremeTechnicalArbitrator;
    mapping(bytes32 => bool) public isUnlocked;
    mapping(address => bool) public certifiedRepairEntity;

    event SchematicsUnlocked(bytes32 indexed deviceId, address requester);
    event DAODecisionOverridden(bytes32 indexed deviceId, address arbitrator);

    constructor(address _regulatoryDAO, address _arbitrator) {
        manufacturer = msg.sender;
        regulatoryDAO = _regulatoryDAO;
        supremeTechnicalArbitrator = _arbitrator;
    }

    function registerRepairEntity(address _entity) external {
        require(msg.sender == manufacturer || msg.sender == regulatoryDAO, "Unauthorized
certification");
        certifiedRepairEntity[_entity] = true;
    }

    function overrideDAODecision(bytes32 _deviceId) external {
        require(msg.sender == supremeTechnicalArbitrator, "Only Supreme Technical Arbitrator
can override");
        isUnlocked[_deviceId] = true;
        emit DAODecisionOverridden(_deviceId, msg.sender);
    }

    function requestRepairAccess(bytes32 _deviceId) external {
        require(!isUnlocked[_deviceId], "Already unlocked");

        bool isOwner = verifyOwnershipViaDID(msg.sender, _deviceId);

        if (isOwner || certifiedRepairEntity[msg.sender]) {
            isUnlocked[_deviceId] = true;
            emit SchematicsUnlocked(_deviceId, msg.sender);
        } else {
            revert("Access denied: Proof of ownership or certification required");
        }
    }
}
```

```

    }
}

function verifyOwnershipViaDID(address _user, bytes32 _deviceId) internal view returns
(bool) {
    revert("Ownership verification oracle not connected or invalid proof provided");
}
}

```

## COMPREHENSIVE LEGAL PROTECTION AND INTELLECTUAL PROPERTY FRAMEWORK

### SECTION 1: COPYRIGHT AND AUTHORSHIP

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### SECTION 2: PATENT PROTECTION

The following innovations are subject to pending patent applications under the Patent Cooperation Treaty (PCT):

Patent Application I: System and Method for Quantifying Physical Harm in Autonomous Systems Using the Kinetic Liability Equation with Strict Liability Base Floor.

Patent Application II: Decentralized Blockchain Architecture with Supreme Technical Arbitration Fallback for Enforcing the Absolute Right to Repair.

### SECTION 3: TRADE SECRETS AND PROPRIETARY ALGORITHMS

The proprietary weighting algorithms for the Kinetic Liability Equation and the specific forensic tracing topologies for hardware failure analysis are maintained as trade secrets under international law.

### SECTION 4: LICENSING FRAMEWORK

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### SECTION 5: ENFORCEMENT AND JURISDICTION

Pending the formal establishment of the International Tribunal for Techno-Criminal Justice (ITTCJ), primary and exclusive jurisdiction for dispute resolution regarding civil liability and techno-criminal matters shall reside within the competent courts of the Arab Republic of Egypt, applying UNCITRAL Model Law principles.

### SECTION 6: AUTHENTIC TEXTS AND INTERPRETATION

This Protocol is drawn up in Arabic, English, and French, all three texts being equally authentic. In the event of divergence, interpretation shall favor the meaning that most effectively protects human bodily integrity, ecological sustainability, and the right to repair. The Spanish, German,

Chinese, and Russian texts are for informational and reference purposes only and hold no legal weight in the event of interpretive divergence.

#### DECLARATION OF ORIGINALITY AND INDEPENDENT RESEARCH

I, Dr. Mohamed Kamal Arafa El Rakhawi, hereby declare that this work is the product of my independent research and original intellectual creation. The conceptual framework of the Elrakhawi Embodied Robotics Protocol, the mathematical formulation of the Kinetic Liability Equation with its strict liability base floor, the legal architecture for Haptic Jurisprudence and Cognitive Liberty, and the drafting of the Universal Declaration of Embodied Robotics are original contributions to the fields of international law, robotics engineering, and global ethics.

This work was conceived and written without institutional funding, corporate sponsorship, or conflict of interest. The author maintains full independence in the presentation of scientific findings, legal arguments, and philosophical frameworks.

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#### END OF DOCUMENT

Dr. Mohamed Kamal Arafa El Rakhawi  
International Researcher  
Ismailia, Arab Republic of Egypt  
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