

## Interaction Session

- Human H
- Robot R
- Commitment(H)
- CollaborativeTask(H,R)

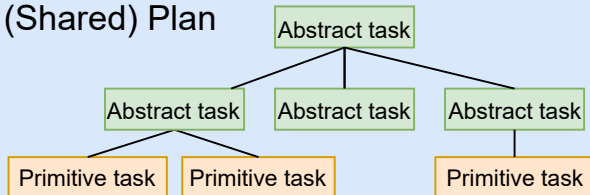
OR

## By itself

- Robot R
- Task(R)

## Task

- (Shared) Goal : desired worldstate
- (Shared) Plan



## Robot Beliefs

- Environment
- Plan progress

## Estimation of Human Beliefs

- Environment
- Plan progress
- Commitment

## Abstract Task

- ID
- Agent
- State
- Decomposition

## Primitive Task

- ID
- Agent
- State
- Predecessors
- Parameters
- Decomposition

## Quality of Interaction

- Session level
- Task level
- Action level

## Recognized Human Actions

- Name
- Parameters
- Progression state

## Executed Robot Action

- Name
- Parameters
- Progression state
- Result