Through reading this week's paper, Fake It to Make It: Exploratory Prototyping in HRI, I have a better understanding of lab 1. As mentioned in the paper, there are three types of prototypes, physical prototypes with human-in-the-loop control, video prototypes, and virtual simulations. We can classify our prototyped interactions as a physical prototype with human-in-the-loop control. The CloneBot we built originally doesn't have any intellectuals, but the operator can control the robot to react accordingly in different scenarios. Under the guidance of the paper, we proposed a scenario in which the miners can ask the CloneBot to turn on lights in dark areas of minefields by clapping hands. Under the control of the operator, the CloneBot can indeed successfully interact with the user but also there are problems of delayed interaction, as suggested in the paper. Moreover, it is hard to really mimic our proposed settings of the scenario. Take the minefield scenario as an example again. In order to really simulate the situation, we need to find a very dark area and make sure the CloneBot closely follow the participant. It is hard to control the CloneBot under such a circumstance and keep the participant unknown of the existence of the operator. Besides, it is also difficult to keep the operator as agile as a real robot.