

Supervision for Human-Robot Interaction

Contents

2.1	Role of the supervisor in the global architecture	1
2.2	The supervisor architecture	2
2.3	Data representation	5

2.1 Role of the supervisor in the global architecture

- Scheme of the complete architecture
- quick description of each module
- quick description of supervisor role

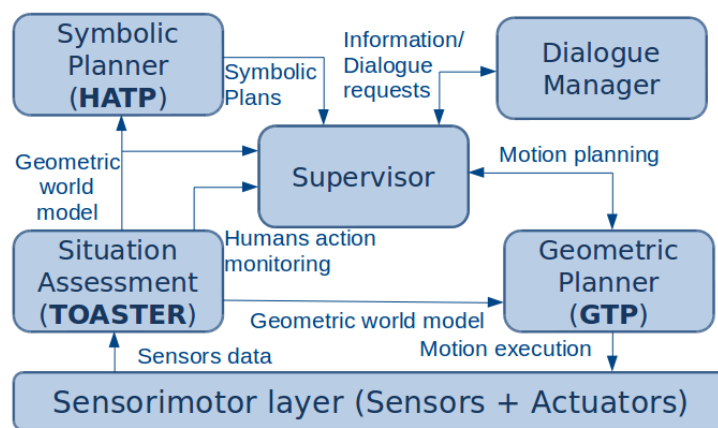


Figure 2.1: The global architecture for human-robot interaction implemented at LAAS-CNRS.

[Lallement 2014]

2.2 The supervisor architecture

- Scheme of the architecture
- introduction datas
- details for each modules

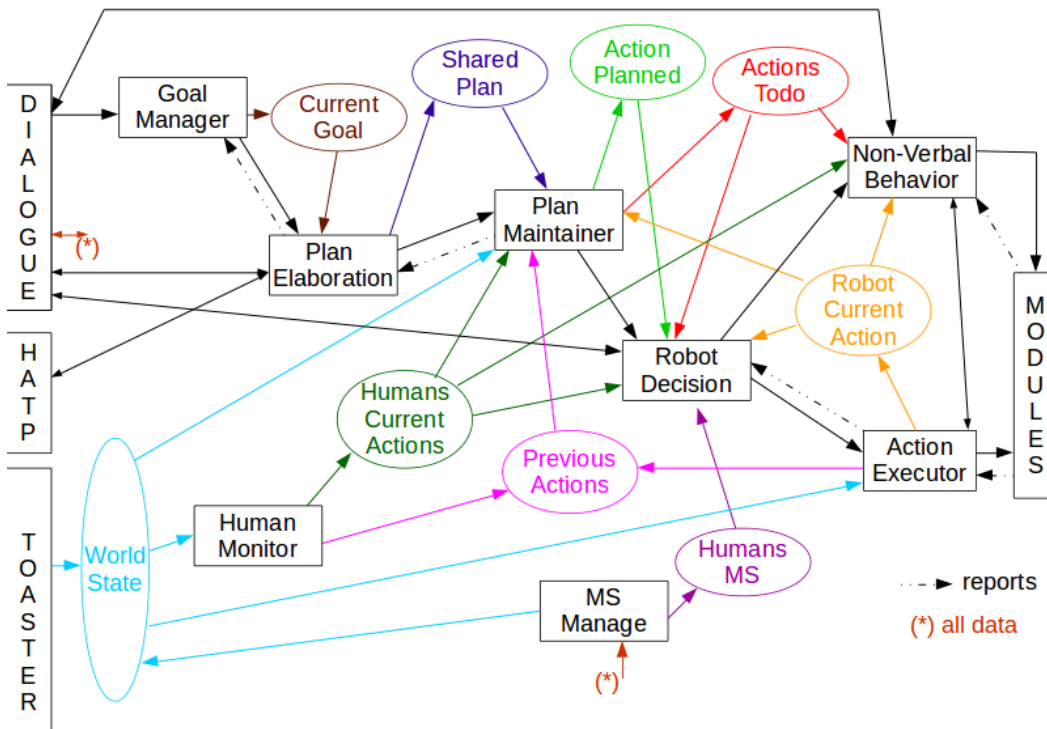


Figure 2.2: Architecture of the supervisor.

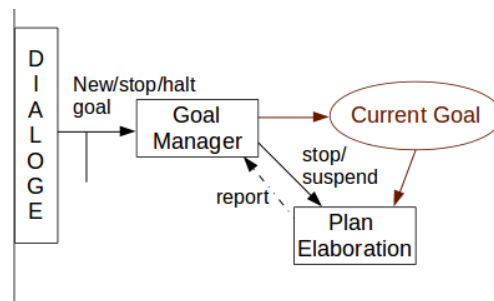


Figure 2.3: Interaction of the Goal Manager with the rest of the supervisor.

Goal Manager

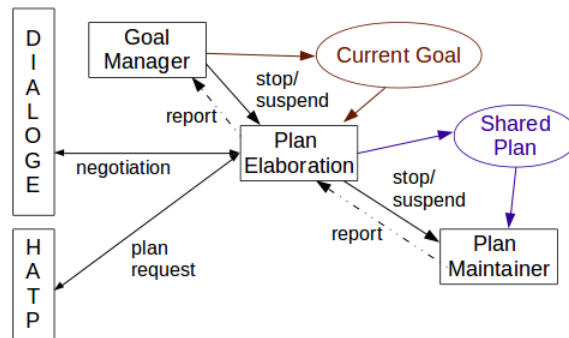


Figure 2.4: Interaction of the Plan Elaboration module with the rest of the supervisor.

Plan elaboration

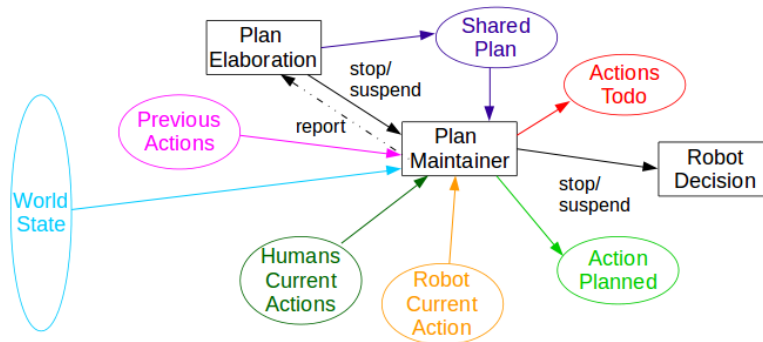


Figure 2.5: Interaction of the Plan Maintainer with the rest of the supervisor.

Goal Manager

Human Monitor

Mental State Manager

Robot Decision

Action Executor

Non-Verbal Behavior

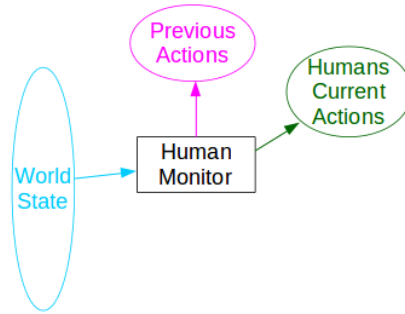


Figure 2.6: Interaction of the Human Monitor module with the rest of the supervisor.

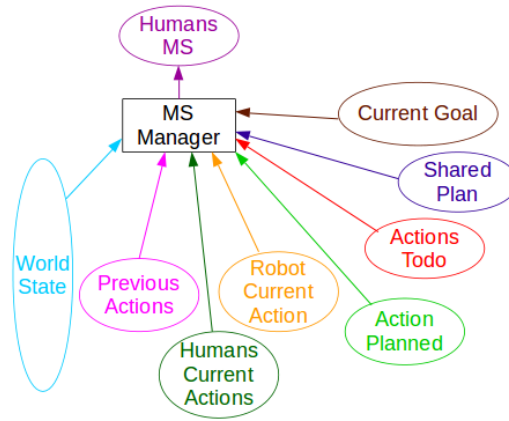


Figure 2.7: Interaction of the Mental State Manager with the rest of the supervisor.

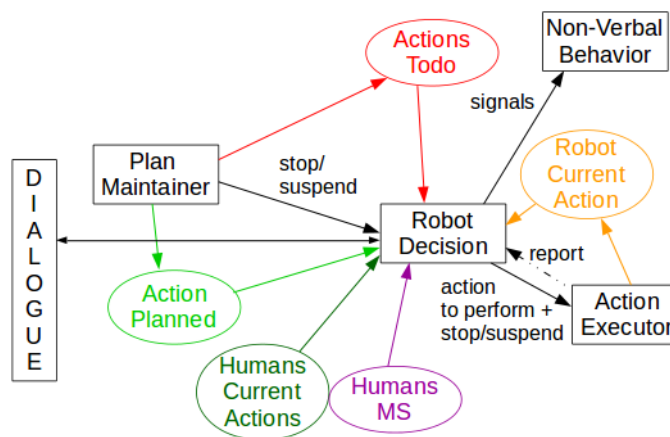


Figure 2.8: Interaction of the Robot Decision module with the rest of the supervisor.

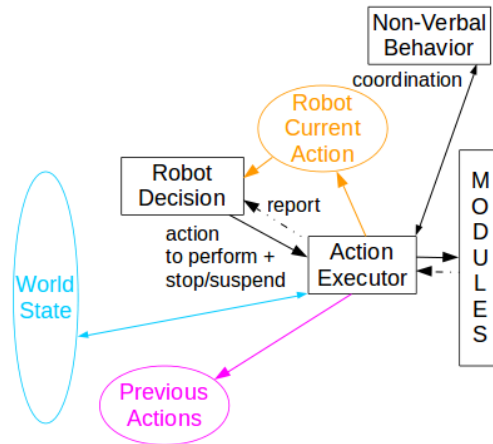


Figure 2.9: Interaction of the Action Executor with the rest of the supervisor.

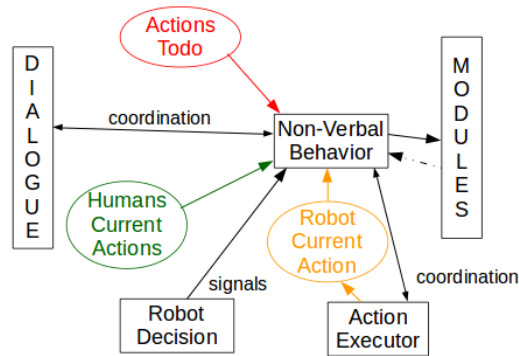


Figure 2.10: Interaction of the Non-Verbal Behavior module with the rest of the supervisor.

2.3 Data representation

- formalization data representation

Bibliography

[Lallement 2014] Raphaël Lallement, Lavindra de Silva and Rachid Alami. *HATP: An HTN Planner for Robotics*. CoRR, 2014. (Cited in page 1.)