Learning to Assess the Cognitive Capacity of Human Partners

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Objectives

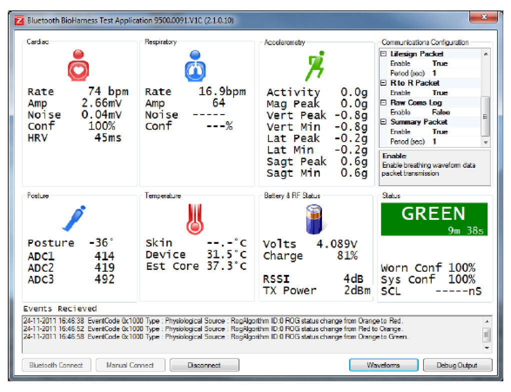
Our goal is to build a model for robots so that they can

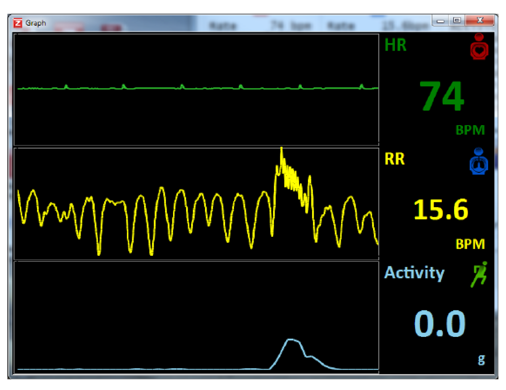
- learn to assess cognitive capacity of a human partner.
- can act autonomously based on that.
- reduce the human decision burden.
- help improving task performance.

Motivations

- Overcome inherent communication barrier between human robot
- Controlling multiple robots becomes impossible: cognitive load, heterogeneous robots
- Complete automation impossible: new task environment
- Robots must asses human cognitive load in human robot-team
- Robots need to assess cognitive capacity of human robot team

Trivial Methods





Trivial fundamental metrics[1] of measuring the behavioral indicators (i.e. ECG,EEG) has following drawbacks:

- hard to set up in generic task environments
- a generic method to assess cognitive load should work with simple metric
- can be useful as baseline

Feature Metrics

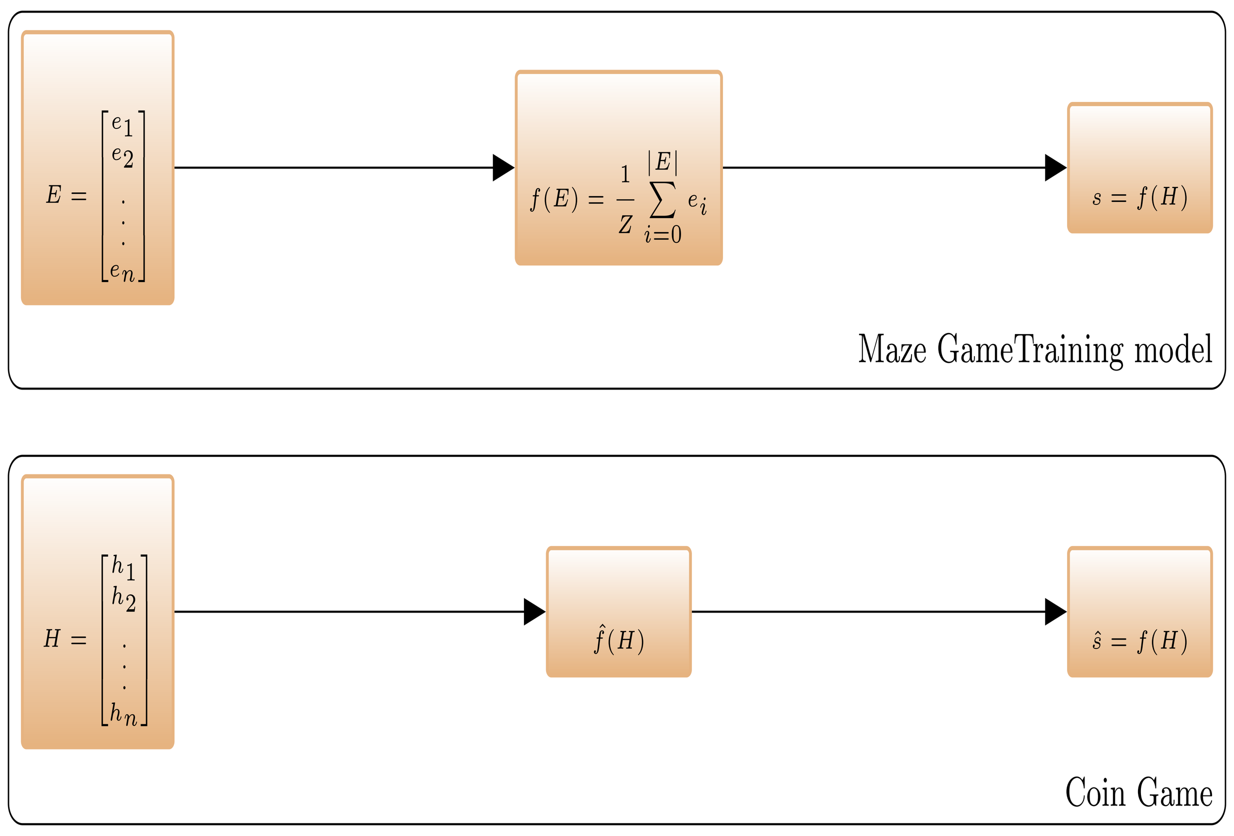
E is measurable environmental features of task success

- e_0 is the *disparity*
- e_1 is the *collision*
- e_2 is the *time delay*

H is human behavioral metrics which are ecologically valid for a navigation direction task

- h_0 is the *decision interval*
- h_1 is the *error correction*
- h_2 is the *franticness*

Overview of the Model



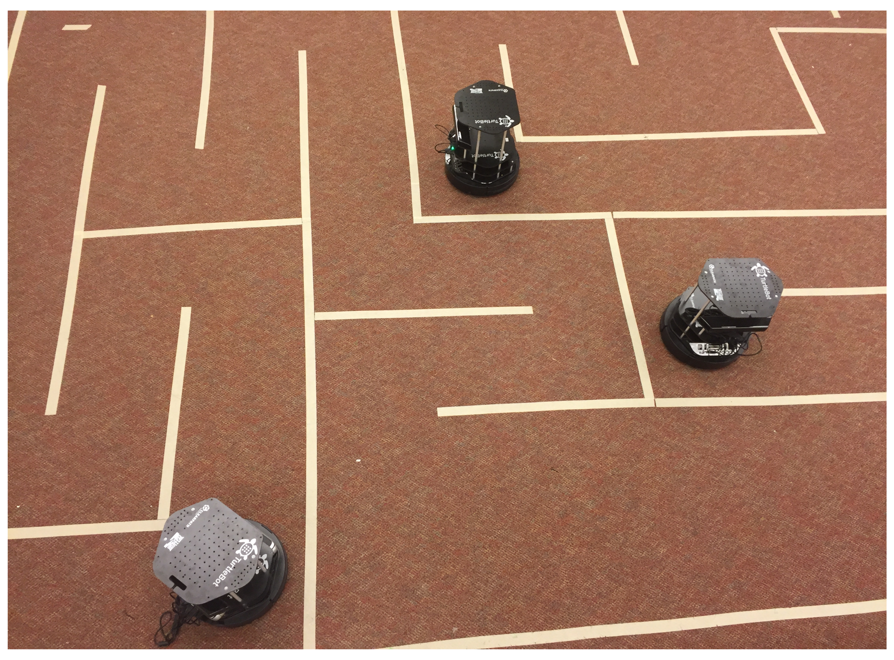


Figure 1: Experimental setup of Maze Game experiment for training

Experiments and Results

Our experiments consisted of two games, maze navigation[2] and coin collection.

Mage Game:

- The task in this game is to complete a maze(Fig.1) by instructing Turtlebot robot
- The game is 2 min. long and collision with walls are negatively rewarded
- The games complexity evolves in succession
- Mage Game was used to collect the metrics in E and calculate the success score s
- The underlying function was modeled using E and s by using Random Forest learner

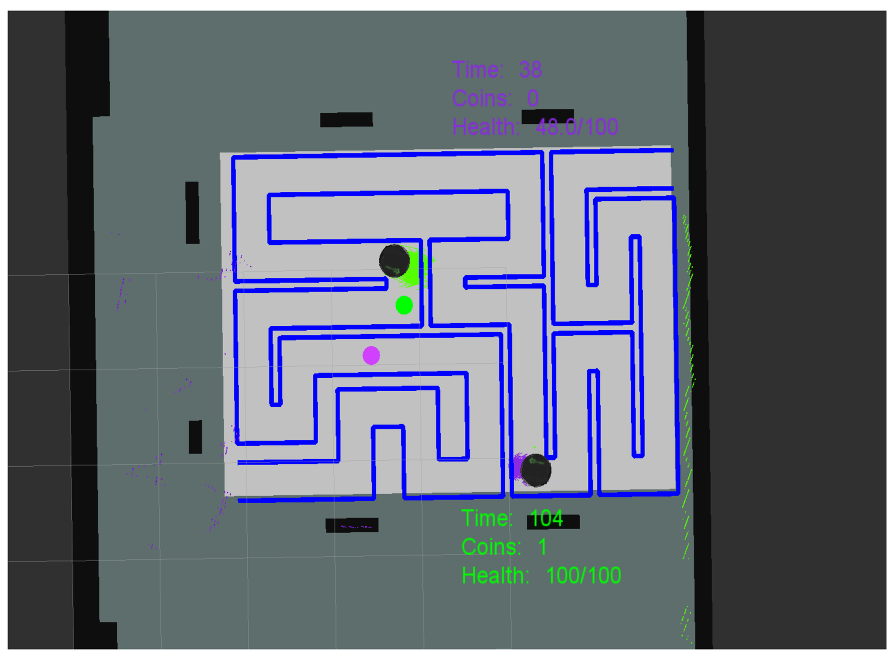


Figure 2: Interface to human operator for Coin game.

Coin Game:

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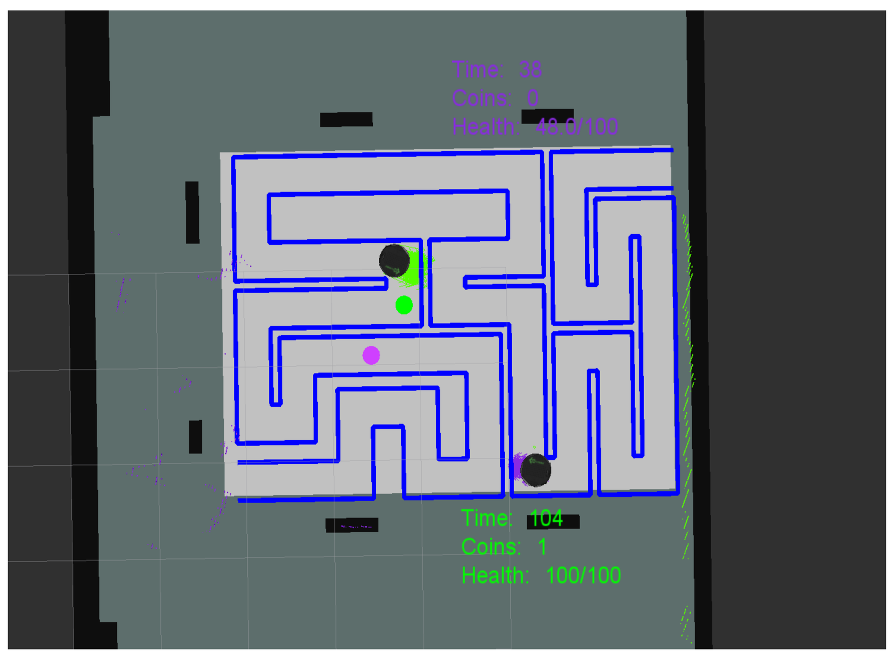


Figure 3: Interface to human operator for Coin game.

Prediction vs Physiologic

- Comparison for truck loading task: Better performance in guided mode

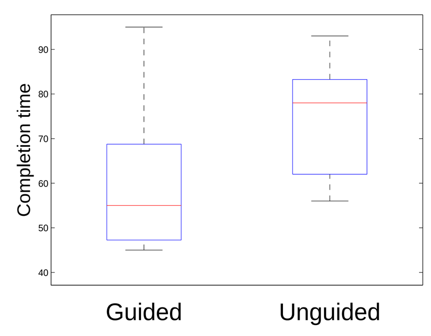
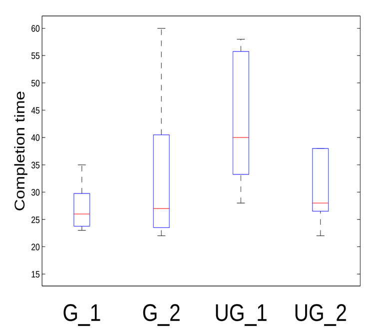


Figure 4: Completion time for the two modes

- Performance comparison between first and second cycle.



References

[1] Dan R Olsen and Michael A Goodrich. Metrics for evaluating human-robot interactions. In *Proceedings of PERMIS*, volume 2003, page 4, 2003.

[2] Christopher Crick, Sarah Osentoski, Graylin Jay, and Odest Chadwicke Jenkins. Human and robot perception in large-scale learning from demonstration. In *Proceedings of the 6th international Conference on Human-Robot Interaction*, pages 339–346. ACM, 2011.

[3] Jacob W Crandall, Michael Goodrich, Dan R Olsen Jr, Curtis W Nielsen, et al. Validating human-robot interaction schemes in multitasking environments. *IEEE Transactions on Systems, Man and Cybernetics, Part A: Systems and Humans*, 35(4):438–449, 2005.