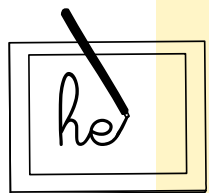


Mutual modelling

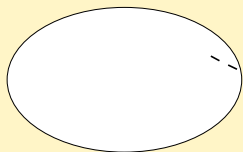
Perception



with-me-ness

Robot's
sensors

child's
feedback



Expected causalities

$P(\text{abstract} \mid \text{perceived})$

M_C

new
variable

M_R

M_{CC}

M_{CR}

Mutual models

Decision

Micro-
behaviour

Activity

...

