

# Work Plan

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# Executive Summary

This document sets out the work plan that will be used to conduct a three-year research project to develop culturally sensitive social robotics for Africa (CSSR4Africa). The objectives of the project are (i) to identify the verbal and non-verbal social and cultural norms of human interaction that are prevalent in countries in Africa, (ii) to encapsulate them in the behavioural patterns of social robots so that they can engage with African people in a manner that is consistent with their expectations of acceptable social interaction, and (iii) to demonstrate these culturally-sensitive social robot behaviours in two use cases: one for giving a tour of a university laboratory, and one for assisting and giving directions to visitors at the reception of a university. In order to ensure that the project objectives can be achieved in the time available, we restrict the scope of the project to the cultures and social practices that are prevalent in Rwanda and South Africa.

# Contents

<b>1</b>	<b>Project Description</b>	<b>1</b>
1.1	Motivation . . . . .	1
1.2	Social Robotics . . . . .	1
1.3	Research Objectives . . . . .	2
1.4	Technical Scope . . . . .	3
<b>2</b>	<b>Work Plan</b>	<b>5</b>
2.1	Approach and Activities . . . . .	5
2.2	Expected Outcomes . . . . .	7
2.3	General Project Information . . . . .	7
2.4	Work Package Descriptions . . . . .	9
	<b>References</b>	<b>74</b>
	<b>Document History</b>	<b>76</b>

# Chapter 1

## Project Description

### 1.1 Motivation

This research project is motivated by the recognition that, for it to be successful, socio-economic development in Africa must be sensitive to people’s culture (Olasunkanmi, 2011). Dignum (2023) drives this home when, in the recently published book *Responsible AI in Africa* (Eke et al., 2023), she says “research and development of AI systems must be informed by diversity, in all the meanings of diversity, and obviously including gender, cultural background and ethnicity”. While the overarching agenda of the inclusive digital transformation of Africa is widely recognized to have the potential to be a positive disruptive influence on many aspects of the lives of African citizens, the transition from recognition of potential to realization of benefits is not a straightforward matter. The transition depends on transforming technological invention into innovation, a process that depends on widespread adoption. However, adoption, especially of AI, depends on trust (Alupo et al., 2022), which, in turn, depends on sensitivity to social and cultural factors (Lee & See, 2004).

Successful innovation also depends on infrastructure. Rose (2010) notes that “infrastructure is the unnoticed precondition for technology innovation”. There are two forms of infrastructure, the physical and the social. The physical infrastructure might include the availability of electrical power, communications networks, or internet connectivity. Of equal importance is the social infrastructure which includes the social conventions that govern people’s behaviour and the practices they find acceptable and unacceptable. Social infrastructure heavily impacts on whether or not an invention is adopted and becomes an innovation that can yield benefits for the local community. Again, social infrastructure includes trust and people’s sense of what is trustworthy.

### 1.2 Social Robotics

There is an increasing need for artificial intelligence technology that is capable of interacting effectively with humans. This includes social robots which serve people in a variety of ways. The global social robotics market was valued at USD 1.98 billion in 2020 and is expected to reach USD 11.24 billion by 2026, registering a compound annual growth rate (CAGR) of 34.34% during the period of 2021-2026 (Research and Markets, 2022).

Social robots are designed to operate in everyday environments, often in open spaces such as hospitals, exhibition centers, and airports, providing assistance to people, typically in the form of advice, guidance, or information. The people interacting with the robot have no special training and they expect the robot to be able to interact with them on *their* terms, not the robot’s. There are two aspects to this expectation.

First, it means that social robots need to be able to interpret the intentions of the people with whom they are interacting. This is difficult to achieve because humans do not necessarily

articulate their specific needs explicitly when they interact with social robots (or, indeed, with other humans). As Sciutti et al. (2018) note, “the ability of the robot to anticipate human behavior requires a very deep knowledge of the motor and cognitive bases of human-human interaction”.

Second, and conversely, humans have expectations of the robot’s behavior and, specifically, they expect the robot to act in a trustworthy, culturally-sensitive, socially-acceptable manner, and they have a distinct preference for robots that exhibit legible and predictable behavior (Sciutti et al., 2018). Since people make predictions based on what they are used to, this is somewhat easier to achieve, provided the robot behaviors are tuned to the socio-cultural context in which they are operating.

People use spatial, non-verbal, and verbal communication when interacting with other people. So too must social robots, if they are to be effective. However, successful interaction requires acceptance and trust, which depend on social and cultural norms. These norms impact on the nature of the robot’s non-verbal and verbal expression as well as its appearance and spatial behaviour. Consequently, they determine the acceptance of social robots and the effectiveness of their interaction (Bartneck et al., 2020). While the case for culturally competent robots has been well made (Bruno et al., 2017b; Khaliq et al., 2018), and while there are studies on cultural differences in the acceptance of robots in the West and East, e.g., by Kaplan (2004); Bartneck et al. (2005); Bruno et al. (2017a), similar studies of the cultural factors that impact of acceptance in Africa have not been reported (Bartneck et al., 2020).<sup>1</sup> This situation will be redressed in the research set out in the work plan in Section 2.

### 1.3 Research Objectives

The successful deployment of social robots in Africa depends on the robots being accepted by African citizens. Culturally sensitive robot behavior, the focus of this project, is a prerequisite for this. As such, this research project is concerned with the second aspect of effective interaction by social robots identified in the previous section: the need for predictable and culturally-acceptable patterns of robot behavior.<sup>2</sup> In other words, the robot must adapt to, or be adapted to the cultural environment. However, rather than attempt to learn these patterns through interaction (a research goal that would involve significantly more effort than is feasible in a project of this size), we aim to identify these patterns through ethnographic research and then embed them in reconfigurable and reusable interaction primitives that can be utilized when developing the interaction behaviors for the application and environment at hand. Thus, we aim to identify the interaction patterns that are socially and culturally acceptable in Africa, and the specific behaviors that will make social robots capable of courteous, respectful, and engaging interaction by reflecting the social and cultural norms of African people.

The factors that underpin effective human-robot interaction include spatial interaction (proxemics, localization and navigation, socially appropriate positioning, initiation of interaction, communication of intent), nonverbal interaction (gaze and eye movement, deictic, iconic, symbolic, and beat gesture, mimicry and imitation, touch, posture and movement, and interaction rhythm and timing), and verbal interaction (speech, speech recognition, language understanding, speech generation) (Bartneck et al., 2020). These spatial, nonverbal, and verbal

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<sup>1</sup>The recent survey by Lim et al. (2021) briefly mentions Egypt, Tunisia, Libya, and Sudan but only to contrast perceptions with the Gulf region when interacting with an Arabic robot.

<sup>2</sup>The ability to interpret the verbal and non-verbal expressions of humans is major challenge in human-robot interaction. Since the development of capabilities for such natural interaction would require much more time and effort than can be accommodated in a project the size of CSSR4Africa, we most interaction by the human to simple requests using the table PC on the Pepper robot. In anticipation of more natural interaction in the future, we include a task to address automated speech recognition for Kinyarwanda speaker but we do not address the interpretation of the human’s gestures and communication behaviors.

interaction factors must reflect the cultural knowledge that would make social robots acceptable in Africa.

This cultural knowledge will also be used to adjust the eight accepted design patterns for sociality in human-robot interaction (Kahn et al., 2008) so that they reflect social and cultural norms in Africa. These design patterns include the initial introduction, didactic communication, moving in motion together, personal interests and history, recovering from mistakes, reciprocal turn taking, physical intimacy, and claiming unfair treatment or wrongful harms.

Having identified the verbal and non-verbal social and cultural norms of human interaction that are prevalent in different countries in Africa, i.e., cultural knowledge, we will encapsulate them in the modes of interaction of social robots so that these robots engage with African people in a manner that is consistent with their expectations of acceptable — courteous and respectful — social interaction, rather than using inappropriate or insensitive social behaviors and modes of interaction from the West or the East.

In pursuing this research, we recognize that there are many different cultures in Africa, with many different norms for deictic, iconic, and symbolic manual gesturing, as well as gestures involving eye gaze, head tilt, eyebrows, and body posture, generally. Similarly, there are many different ways in which spoken language can express nuances of meaning by modulating amplitude and timbre. In order to ensure that the project objectives can be achieved in the time available, we restrict the scope of the project to the cultures and social practices that are prevalent in Rwanda and South Africa.

The outcomes of the research will take the form of a suite of software primitives, integrated in an application programming system architecture, and a set of design patterns that can be recruited during human-robot interaction, deploying the spatial, non-verbal and verbal communication channels that are best suited to the social and cultural needs of the interaction.

The software primitives, system architecture, and design patterns will be evaluated in two complementary use cases. Each use case will be conducted in two phases, so that evaluation after the first phase can provide feedback and allow the results of the research to be adjusted and improved, if necessary.

## 1.4 Technical Scope

It is increasingly accepted that AI systems need to understand, and interact in, the social world of humans. This is particularly true in robotics, which is viewed by many as “cognition-enabled transferable embodied AI” (euROBIN, 2023) and, especially, in social robotics. As we noted above, effective interaction is essential for acceptance, trust, and adoption. This implies that social robots must be able to recognize cultural traits in humans, infer their intentions, and behave in a manner that is culturally legible and predictable by adhering to social and cultural norms.

A complete culturally competent robot requires at least five elements (Bruno et al., 2017a), as follows.

1. Cultural knowledge representation.
2. Culturally sensitive planning and action execution.
3. Culturally aware multimodal human-robot interaction.
4. Culture-aware human emotion recognition.
5. Culture identity assessment, habits, and preferences.

This research project focusses on the first three of these, i.e., the generation of culturally sensitive robot behavior. Specifically, the project does not address the challenge of learning these behaviors from observation, i.e., learning cultural knowledge through interaction. Instead, the

approach in this project is to catalogue the behaviors based on ethnographic research and embed them in reconfigurable software design patterns. In the short term, this is a more tractable approach and will produce reusable results, while still being compatible with the goal of developing culturally competent robots by combining top-down and bottom-up approaches based on the predetermined profiles of a cultural group and the cultural profiles derived from the behaviors of individuals, respectively (Khaliq et al., 2018).

# Chapter 2

## Work Plan

### 2.1 Approach and Activities

We adopt both a user-centric perspective and an agile and iterative approach in this project. This is reflected in the work plan; see the Pert chart in Figure 2.1 and the list of work packages in Table 2.1.

WP1 is user-driven and focusses on identifying the cultural and social norms, i.e., the cultural knowledge, that define respectful, engaging interaction in African countries. It will achieve this through ethnographic user studies that create the data that will then define the development of Africa-centric modes of human-robot interaction and design patterns for courteous and respectful sociality. The cultural knowledge and design patterns are used to specify the robot behaviours in WP5, which are used in the two demonstration and evaluation use cases in WP6. The robot sensing functionality required for interaction is developed in WP4. The integration of all functionality in a coherent system architecture is carried out in WP3, while the specification of the interaction scenarios is carried out in WP2. The interpretation of these scenarios is effected by the robot behaviors subsystem developed in WP5. Monitoring research progress, meanwhile, is also done in WP6 through user studies that test and validate the targeted use case functionality at the end of years 2 and 3 of the project, taking appropriate action after year 2 to adjust and augment each element in WP1 - WP5 in order to improve the performance in the use cases in the subsequent phase. The timeline also highlights this iterative development; see the Gantt chart in Figure 2 in Section 2.4, where detailed work package descriptions are also provided.

Table 2.1: List of work packages

WP No.	Work Package Title	Lead Partner	Person Months	Start Month	End Month
1	African Cultural Knowledge		5.64	1	27
2	Interaction Scenario Specification		13.50	3	27
3	System Architecture & Systems Engineering		13.50	3	33
4	Robot Sensing		13.50	3	33
5	Robot Behaviors		13.50	3	33
6	Use Case Demonstration and Evaluation		6.15	1	36
7	Dissemination and Impact		2.75	1	36
8	Project Management		1.31	1	36





Figure 2.1: PERT chart showing the dependencies between the technical work packages; note the iterative development cycle.

For the ethnographic study of the cultural knowledge that defines respectful, engaging interaction in African countries that will be carried out in WP1, we perform these studies using two independent groups, and cross-validate the results, with one group validating the other group’s results, adjusting appropriately, if necessary. In addition, we plan on engaging an external expert in ethnographic research in developing countries to ensure the validity of our approach and adapt it, as required.

In terms of technical development, we plan to adopt the development methodology and outline functional architecture for a culturally competent robot proposed by Bruno et al. (2017b), using the culture knowledge ontology proposed by Bruno et al. (2019) as a foundation.

From a software engineering perspective, CSSR4Africa will adopt the current best practice in robot software development based on component-based robotic engineering (Brugali & Scandurra, 2009; Brugali & Shakhimardanov, 2010) and adapted from established component-based software engineering of component-based software engineering (Heineman & Council, 2001; Szyperski, 2002). With a focus on effective integration, the CSSR4Africa system will adhere to the best practice of making components composable (the property that makes it easily integrated into a larger system) and systems compositional (the property to exhibit predictable performance and behaviour if the performance and behaviour of the components are known).

We will use ROS, a globally-used implementation of component-based software engineering (CBSE). Furthermore, we will adopt an integration-focussed approach to the development of the system architecture (Vernon et al., 2015) based on CBSE, in general, and the component-port-connector model (i.e., the publish and subscribe model), in particular. In essence, then, we propose an adaptive, compositional agent-based message-passing software architecture to bridge WP4 & WP5 functionality and WP6 use-case behaviors.

All software will adhere to a project-specific set of software specification, design, coding, and documentation standards. These standards will also be applied to every module or subsystem that comprises each of the two primary subsystems (robot sensing and robot behaviours). In this way, the complete CSSR4Africa system will be based on a modular decomposition with the same interface protocol and software engineering standards applying at every level of decomposition. This approach facilitates transparent configuration and incremental integration & test of the complete system, from component, to subsystem, to system as a whole.

This approach ensures that those responsible for these subsystems have sufficient freedom

to choose the design that suits the subsystem needs best while at the same time requiring them to adhere to project-wide standards of software engineering and quality assurance.

## 2.2 Expected Outcomes

The CSSR4Africa research project will produce four measurable outcomes, as follows.

1. The identification of the cultural factors that impact on the acceptance of social robots in Africa, the constraints they impose on spatial, non-verbal, and verbal communication and social behavior, and the preferred behavioral traits that are considered appropriate for human-robot interaction in Africa.
2. The development of a suite of culturally-sensitive robot interaction primitives derived from the cultural knowledge, implemented on a Pepper humanoid robot <sup>1</sup> These primitives will include, for example, maintenance of appropriate interpersonal distance, adjustment of head and gaze direction, deployment of arm movement and hand gestures, and adoption of body posture.
3. The creation of a set of design patterns for culturally-sensitive social interaction in human-robot interaction, tuned to the preferences of African people.
4. A demonstration of the effectiveness of these design patterns in two complementary use cases.

We will validate the research by developing a use case that involves a humanoid robot giving a guest or group of guests a tour of a typical university laboratory. For this, we will specify and implement the functional requirements of the tour (for example, what exhibits to show, what to say to explain their purpose, how to navigate from one exhibit to another) and then factor in the non-functional requirements that address the culturally sensitive interaction while executing the functional elements of the tour (for example, how to greet and address the guest, how to maintain their engagement, how to draw their attention to the exhibit, and how to lead them from one exhibit to another). A second use case involving the robot taking the role of a receptionist that can provide information and directions to visitors will also be developed.

As noted in Section 1.1, the potential benefits of these research outcomes include AI technology, i.e., social robotics, that is culturally sensitive and therefore much more likely to be accepted and adopted, contributing to the *inclusive* digital transformation of Africa while simultaneously building research capacity by providing a foundation for future research in human-robot interaction in the form of reusable software and by exposing students to the various aspects of successful research practice. Since the software will be made available on GitHub with an open source licence, it can be freely used by researchers and software developers in Africa. This will make a significant contribution to the capacity of these roboticists to develop their own bespoke culturally-sensitive social robot applications helping to create new software development jobs in social robotics. This will position African software developers to compete for their share of a large and quickly growing global market in social robotics.

## 2.3 General Project Information

### Project Management Plan

Work package 8 is dedicated to project management, with separate tasks for project coordination and communication (8.1), administration (8.2), risk management (8.3), the creation of a consortium agreement (8.4), and the creation of a gender action plan (8.5). Details of the work involved in each task can be found in the work package descriptions below.

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<sup>1</sup><https://www.aldebaran.com/en/pepper>. Note: the ROS package for Pepper only supports the legacy ROS Indigo distro. CMU-Africa is porting this to ROS Melodic and investigating alternative work-arounds.

## Facilities

We will use the Pepper social robot from Aldebaran, a part of the United Robotics Group, to develop and validate the culturally-sensitive spatial, non-verbal, and verbal behaviors.

## Dissemination Strategy

Work package 7 is dedicated to dissemination and impact, with targetted tasks Online Presence (7.1), Dissemination Activities (7.2), Open-Source Software, Data, and Designs (7.3), and an end-of-project Summer School (7.4). Details of the work involved in each task can be found in the work package descriptions.

## Measures of Success and Assessment

The evaluation of the success of the project is carried out in work package WP6, Task 6.2 Use Case Evaluation and Task 6.3 Use Case Re-Evaluation. The focus of this evaluation is to assess the degree to which African people rate the interaction experience with social robots equipped with the Africa-centric traits developed in this project higher than interaction experience with social robots equipped only with universal traits. Evaluation will explore the *holistic interaction experience*, i.e., the three perspectives on social interaction with robots in (Young et al., 2011). User studies will be used for evaluation in the first phase, while a combination of user, observational, and, if feasible, ethnographic studies in the second phase. Both between-subject and within-subject design will be used, with assessment based on the Robot Social Attribute Scale (RoSAS) (Carpinella et al., 2017).

## Project Risks

Risks and risk mitigation plans are outlined in Table 4 below. Task 8.3 in WP8 Project Management is dedicated to risk management.

## Project Work Plan

The project work plan is summarized in the Gantt chart in Figure 2. Detailed work package descriptions are provided below, along with a list of deliverables in Table 2, a list of milestones in Table 3, risk mitigation strategies in Table 4, and a summary of effort by partner in Table 5.

## Collaboration

Effective collaboration between the PI, the Co-PI, and their research assistants will be achieved by several means, e.g., daily communication using the project Discord platform with channels for each task, weekly monitoring of progress, three-monthly in-person meetings, and six-monthly progress report, and risk management activities (see WP8, Tasks 8.1 and 8.3). A significant amount of the work required will be carried out in student projects, e.g., summer internship projects and student research projects. These will, where appropriate, be co-supervised by faculty from both CMU-Africa and Wits. Students will be encouraged to engage in collaborative software development on the robots at each site.

## 2.4 Work Package Descriptions

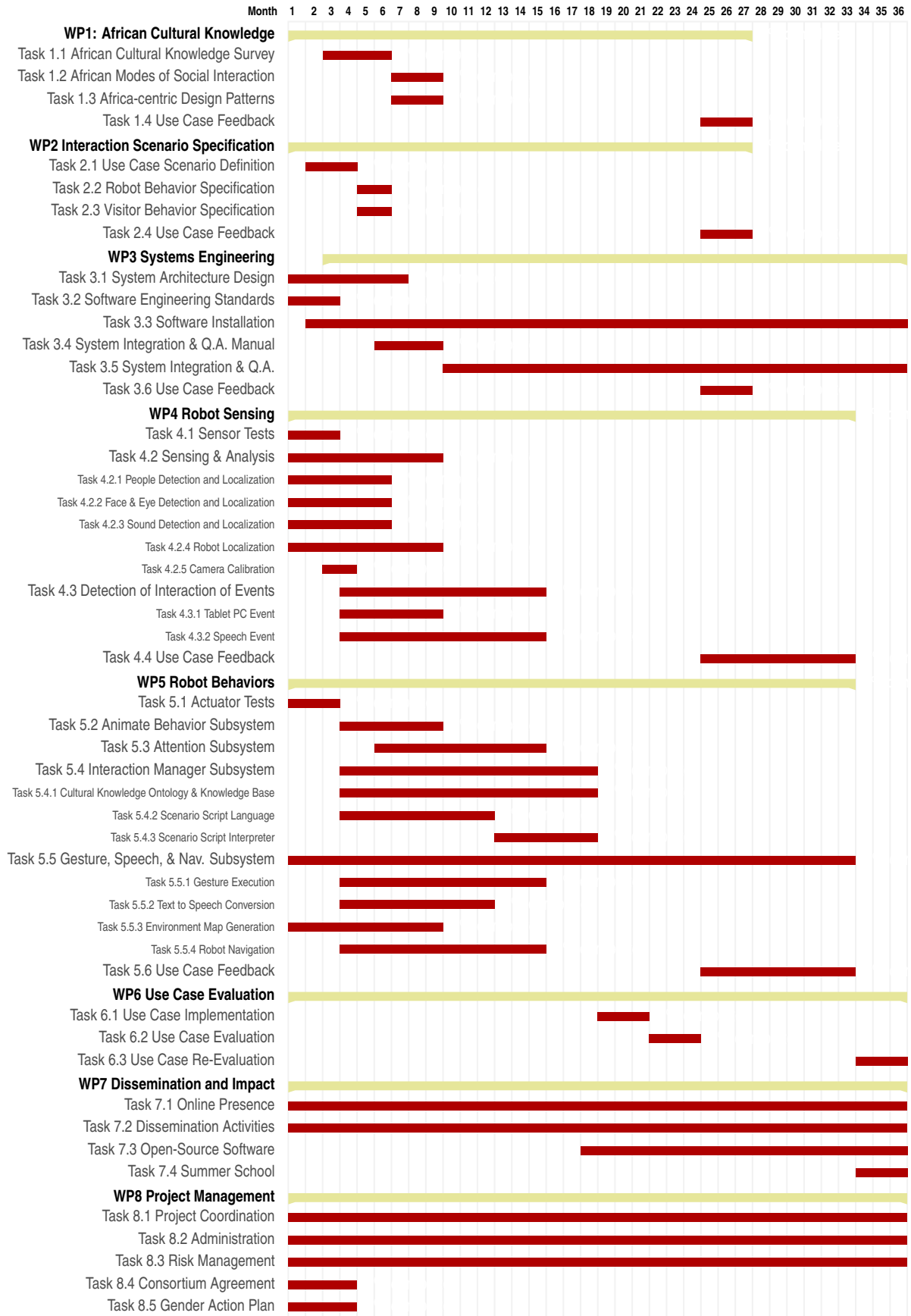


Figure 2: Gantt diagram showing the tasks in each work packages

Work Package Number	1
Work Package Title	African Cultural Knowledge

## Objectives

1. Identify the knowledge that is required to effect culturally-sensitive interaction in Rwanda and South Africa.
2. Use this cultural knowledge to identify, adjust, and augment the spatial, non-verbal, and verbal modes of interaction that impact the effectiveness of human-robot interaction (Bartneck et al., 2020).
3. Use this cultural knowledge to adapt and augment the eight design patterns for sociality in human-robot interaction proposed by Kahn et al. (2008).

## Description of Work

### **Task 1.1: African Cultural Knowledge Survey (M3–M6)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to carry out an ethnographic study with the goal of identifying the knowledge that is required to effect culturally-sensitive interaction in Rwanda and South Africa. This will form the basis of the general, population-based cultural knowledge base for culturally sensitive human-robot interaction. This objective will be achieved by identifying the best practice for such ethnographic studies, preparing a plan of action to conduct the study, validating the plan with a qualified social scientist or ethnologist, adapting the plan as necessary, conducting the study, extracting the key results, summarizing the cultural knowledge, and validating it with a control group of people. The outcome of this task is described in Deliverable D1.1.

### **Task 1.2: African Modes of Social Interaction (M7–M9)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is adjust or augment the spatial, non-verbal, and verbal modes of interaction that impact the effectiveness of human-robot interaction in Africa, focussing on Rwanda and South Africa, by incorporating cultural knowledge. This objective will be achieved by first cataloging the modes of interaction specified by Bartneck et al. (2020), analysing them to identify ways in which they should be adjusted to reflect cultural knowledge. A gap analysis will then be conducted to identify cultural knowledge that has not been taken into consideration. Any gaps will then be addressed by augmenting the existing modes of interaction. The task uses the cultural knowledge identified in Task 1.1 as documented in Deliverable D1.1. The outcome of this task is described in Deliverable D1.2.

## Description of Work (continued)

### **Task 1.3: Africa-centric Design Patterns (M7–M9)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to adapt and augment the eight design patterns for sociality in human-robot interaction proposed by Kahn et al. (2008) by incorporating cultural knowledge. This objective will be achieved by analysing the eight design patterns to identify ways in which they should be adjusted to reflect cultural knowledge. A gap analysis will then be conducted to identify cultural knowledge that has not been taken into consideration. Any gaps will then be addressed by augmenting the existing design patterns. The task uses the cultural knowledge identified in Task 1.1 as documented in Deliverable D1.1. The outcome of this task is described in Deliverable D1.3.

### **Task 1.4: Use Case Feedback (M25–M27)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to update the African cultural knowledge, the Africa-centric modes of interaction, and the Africa-centric design patterns for sociality in human-robot interaction based on feedback from the use case evaluations. This objective will be achieved by identifying any cultural knowledge that has not been included in the existing knowledge and identifying any cultural knowledge in the knowledge base that should be adjusted. The knowledge base will be updated, and the modes of interaction and design patterns will be amended accordingly. The task uses the outcomes of Task 6.2, as documented in Deliverable D6.2. The outcome of this task is described in revised versions of Deliverables D1.1, D1.2, and D1.3.

## List of Deliverables

Number	Deliverable Title	Lead Partner	Delivery Month
D1.1	African Cultural Knowledge, versions 1 and 2		M6, M27
D1.2	African Modes of Social Interaction, versions 1 and 2		M9, M27
D1.3	Africa-centric Design Patterns, versions 1 and 2		M9, M27
D1.4	Updates to Deliverables D1.1, D1.2, and D1.3		M27

## Description of Deliverables

### D1.1 African Cultural Knowledge

*Deliverable type: report.*

This deliverable represents the outcome of Task 1.1. It comprises a catalogue of general cultural knowledge<sup>2</sup> in the form of behaviours, activities, actions, and movements<sup>3</sup> that are either culturally sensitive or culturally insensitive. The culturally-sensitive behaviors, activities, actions, and motions will be used to define the culturally sensitive African modes of social interaction in Deliverable D1.2 and the Africa-centric design patterns in Deliverable D1.3. It will be formalized in the culture knowledge ontology and knowledge base in Deliverable D5.4.1.

### D1.2 African Modes of Social Interaction

*Deliverable type: report.*

This deliverable represents the outcome of Task 1.2. It comprises a catalogue of modes of social interaction that are culturally sensitive, based on the cultural knowledge contained in Deliverable D1.1. The modes of interaction include spatial interaction (proxemics, localization and navigation, socially appropriate positioning, initiation of interaction, communication of intent), nonverbal interaction (gaze and eye movement, deictic, iconic, symbolic, and beat gesture, mimicry and imitation, touch, posture and movement, and interaction rhythm and timing), and verbal interaction (speech, speech recognition, language understanding, speech generation) (Bartneck et al., 2020).

### D1.3 Africa-centric Design Patterns

*Deliverable type: report.*

This deliverable represents the outcome of Task 1.3. It describes any adjustments that need to be made to the eight accepted design patterns for sociality in human-robot interaction proposed by Kahn et al. (2008) so that they reflect social and cultural norms in Africa. The adjustment will be based on the cultural knowledge reported in Deliverable D1.1. These design patterns include the initial introduction, didactic communication, moving in motion together, personal interests and history, recovering from mistakes, reciprocal turn taking, physical intimacy, and claiming unfair treatment or wrongful harms. Additional design patterns will be added, if necessary, again based on the cultural knowledge contained in Deliverable D1.1.

### D1.4 Updates to Deliverables D1.1, D1.2, and D1.3

*Deliverable type: report.*

This deliverable represents the outcome of Task 1.4. Based on the evaluation of the two use cases in work package WP6, and the material in Deliverable D6.2 in particular, it sets out any changes or additions that need to be made to the African cultural knowledge, the Africa-centric modes of interaction, and the Africa-centric design patterns for sociality in human-robot interaction in Deliverables D1.1, D1.2, and D1.3, respectively.

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<sup>2</sup>We follow the lead of Bruno et al. (2017b) in distinguishing between general cultural knowledge, which is typically valid for many people in a given culture, and specific cultural knowledge, which is based on one or a small number people.

<sup>3</sup>We define a behavior as a pattern of activity, an activity as a sequence of actions, an action as a goal-directed sequence of motions, and a motion as a change in effector pose, subject to constraints, e.g., trajectory or biological velocity and acceleration profile.

Work Package Number	2
Work Package Title	Interaction Scenario Specification

## Objectives

1. To develop the two use case scenarios — lab tour guide and receptionist — and define detailed procedures for their execution.
2. To specify in detail the desired robot behavior from the point of view of the the robot's manager, i.e., the person responsible for assigning the role of lab tour guide or receptionist to the robot.
3. To specify in detail the expected visitor behavior, i.e., the expected interactions by the person to whom the tour is being given or by the person at reception. As noted already, this project does not address the interpretation of natural non-verbal human communication such as gestures and emotions. While limited automated speech recognition will be investigated, the main form of interaction by the human will be through the tablet PC on the robot.

## Description of Work

### **Task 2.1: Use Case Scenario Definition (M2–M4)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is define the two use cases: lab tour guide and receptionist. This objective will be achieved by detailing the aim of the use case scenario, the setting, and the procedure: a step-by-step implementation of the scenario. The implementation will be based on a structured walk-through of all the interactions that instantiate the scenario. The purpose of the walk-through is to unwrap the interaction in each use case into micro-steps of elementary perceptions as seen by the robot (from the perspective of the robot's manager) and actions by the interaction partner, i.e., the visitor. Once this timeline of elemental perceptions and actions has been unwrapped, we can then identify the measurable sensory indicators required to parameterize and quantify the information about visitor that is necessary to allow the robot to interact effectively (i.e., in a culturally sensitive manner) with her or him, e.g., locating the position off the visitor, their face, and eyes. As noted already, the main form of interaction by the human will be through the tablet PC on the robot and, optionally, through limited spoken requests and instructions, implemented with automated speech recognition. This unwrapped walk-through provides the baseline data for tasks T2.2 and T2.3. The outcome of this task is described in Deliverable D2.1.



## Description of Work (continued)

### **Task 2.2: Robot Behavior Specification (M5–M6)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to generate a list of desired robot behaviors, i.e., sequences of actions, that the gesture, speech, and navigation subsystem in WP5 will later synthesize. This objective will be achieved by analysing the use case scenarios defined in Deliverable D2.1, producing a detailed specification of the culturally-sensitive behaviors the robot has to execute in WP5. These will include, for example, greeting and welcoming actions, introductions, and polite attention-grabbing behaviors, task initiation, task demonstrations, feedback behaviors, and alarm behaviors. This task uses the outcome of Task 2.1, as documented in Deliverable D2.1, as well as Deliverable D1.2 African Modes of Social Interaction and D1.3 Africa-centric Design Patterns. The outcome of this task is documented in Deliverable 2.2.

### **Task 2.3: Visitor Behavior Specification (M5–M6)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to specify the visitor's interaction behaviors that will to be facilitated in the use case scenarios. As noted, this project does not address the interpretation of natural non-verbal human communication such as gestures and emotions. While limited automated speech recognition will be investigated, the main form of interaction by the human will be through the tablet PC on the robot. Consequently, the primary goal is to characterize the inputs that the visitor can effect using the tablet PC and through simple spoken utterances. This objective will be achieved by analysing the use case scenarios defined in Deliverable D2.1, producing a detailed specification of the visitor actions that can trigger a response by the robot, and the expected action to be taken by the robot. This mode of interaction will be modelled by a state transition diagram, capturing the visitor inputs and the appropriate robot responses. This task uses the outcome of Task 2.1, as documented in Deliverable D2.1. The outcome of this task is documented in Deliverable D2.3.

### **Task 2.4: Use Case Updates (M25–M27)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to update the use cases based on feedback from the use case evaluations. This objective will be achieved by identifying any adjustments that are necessary to improve the acceptability, feasibility, and cultural sensitivity of the use cases. The task uses the outcomes of Task 6.2, as documented in Deliverable D6.2, The outcome of this task is summarized in Deliverable D2.4 and incorporated in revised versions of Deliverables D2.1, D2.2, and D2.3.

## List of Deliverables

Number	Deliverable Title	Lead Partner	Delivery Month
D2.1	Use Case Scenario Definition		M4, M27
D2.2	Robot Behavior Specification		M6, M27
D2.3	Visitor Behavior Specification		M6, M27
D2.4	Use Case Updates		M27

## Description of Deliverables

### D2.1 Use Case Scenario Definition

*Deliverable type: report.*

This deliverable represents the outcome of Task 2.1. It presents a detailed scenario definition for the two use cases: lab tour guide and receptionist. It describes the aim of the use case, the setting, the procedure, and the measurable variables. It provides the basis for the robot behavior specification (D2.2) and the visitor behavior specification (D2.3). The report includes a walk-through of the scenario, providing a decomposition into a time sequence of elementary robot actions. For each action, the deliverable will specify the following.

1. The set of triggers for the action, e.g., input from the robot's manager or visitor using the tablet PC on the robot, speech input, or movements of the visitor.
2. The sensory cues that characterize each trigger, including tablet PC inputs.
3. The exact sequence of movements, expressions, or vocal output that constitute the robot action and their associated sensory cues.
4. The goal of the action, i.e., the expected change in the environment, the response of the visitor, or the robot's manager.
5. The sensory cues that characterize the goal of the action; in each case, there may be multiple triggers and responses.

The report will also detail the layout of the environment in which the scenarios are set.

### D2.2 Robot Behavior Specification

*Deliverable type: report.*

This deliverable represents the outcome of Task 2.2. It specifies in detail the robot behavior required for the targetted use cases. It is based on the walk-throughs documented in Deliverable D2.1, assigning actions to labelled robot behaviors based on shared characteristics, such as triggers, movements or expressions, and goals. These actions will reflect the culturally sensitive requirements specified in Deliverable D1.2 African Modes of Social Interaction and D1.3 Africa-centric Design Patterns. This report provides the requirements for work package WP5 on robot behaviours. Specifically, it provides the basis for specification of robot behaviours in Task 5.4.2 Scenario Script Language and the execution of behaviors and their constituent actions in the gesture, speech, and navigation subsystem in Task 5.5, as well as the selection of behaviors in the use case implementation in Task 6.1.

## Description of Deliverables (continued)

### **D2.3 Visitor Behavior Specification**

*Deliverable type: report.*

This deliverable represents the outcome of Task 2.3. It specifies in detail the visitor's interaction behaviors that will be facilitated and encapsulated in the use case scenarios. It is based on the walk-throughs documented in Deliverable D2.1, assigning actions to labelled visitor interactions, such as interaction with the tablet PC on the robot and simple spoken utterances. Interaction using the tablet PC on the robot will be modelled by a state transition diagram, capturing the visitor inputs and the appropriate robot responses. It also lists the spoken utterances that will be accommodated and the required responses by the robot. This report provides the requirements for work package WP4 on robot sensing, specifically Tasks 4.3.1 Tablet PC Event and 4.3.2 Speech Event.

### **D2.4 Use Case Updates**

*Deliverable type: report.*

This deliverable represents the outcome of Task 2.4. Based on the evaluation of the two use cases in work package WP6, and the material Deliverable D6.2 in particular, it sets out any changes or additions that need to be made to the used case scenario definition, the robot behavior specification, and the visitor behavior specification in deliverables D2.1, D2.2, and D2.3, respectively.

Work Package Number	3
Work Package Title	Systems Engineering

## Objectives

1. Design a software architecture that will facilitate the integration of the results of the project into a complete operational culturally sensitive social robotics system.
2. Formalize the integration process by identifying appropriate software engineering standards and quality assurance procedures.
3. Carry out this integration and quality assurance process.

## Description of Work

### Task 3.1: System Architecture Design (M1–M7)

*Lead Partner:*

*Participating Partner:*

The objective of this task is to design the system architecture to integrate the functionality developed in work packages WP4 and WP5, providing the necessary infrastructure to implement each of the two use cases, including domain- and task-specific knowledge. This objective will be achieved by identifying each of the architecture subsystems, specifying their functionality, and defining their interfaces using a component-based software engineering (CBSE) approach (Vernon et al., 2015). We plan to adopting the development methodology and outline functional architecture for a culturally competent robot proposed by Bruno et al. (2017b), using the ontology proposed by Bruno et al. (2019) as a foundation. The task is guided by the requirements encapsulated in Deliverables D2.1 User Case Scenario Definition, D2.2 Robot Behavior Specification, and D2.3 Visitor Behavior Specification. Architecturally, the software developed in work packages WP4 and WP5 will be viewed as a modular subsystems. The goal of this task is to specify the functionality of each of these subsystems and to define their interfaces, i.e., the manner in which data and control signals are input to and output from these subsystems. These interfaces will be specified at both a high level of abstraction (e.g., what data is input and output and how it is represented) and at a low-level of abstraction (how this data is exposed through subsystems interfaces and how the functionality of the subsystem can be externally configured by other subsystems). The low-level interface and functional configuration facilities will be effected using the ROS (Robot Operating System). Interface design and module specification will be done in collaboration with the respective module development tasks in work packages WP4 and WP5. The outcome of this task is described in Deliverable D3.1.

## Description of Work (continued)

### **Task 3.2: Software Engineering Standards (M1–M3)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to define a set of project standards governing the specification, design, documentation, and test of all software to be developed in work packages WP4 and WP5. The specification standards will address functional definition, data representation, and module / sub-system behaviour. Design standards will focus on the decoupling of functional computation, module communication, external module configuration, and inter-module coordination. To maximize compositionality, a best-practice component-based software engineering model. To enhance dependability, software associated with normal flow of execution and exception handling will be separated. Software test strategies will include black-box unit testing, white-box structural testing at the sub-system level, and regression testing to ensure backward compatibility. Acceptance tests will be carried out on the basis of the required behaviours for the two use cases. In addition, this task will define the procedures whereby software developed in work packages WP4 and WP5 is submitted for integration, checked against standards, and tested. These procedures will also address the actions to be taken as a result of this integration and quality assurance process. This objective will be achieved by adapting and adopting standards using in previous research projects RobotCub<sup>4</sup> and DREAM.<sup>5</sup> The outcome of this task is described in Deliverable D3.2.

### **Task 3.3: Software Installation (M2–M36)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to document the process for the installation and execution of the software required to instantiate all or part of the CSSR4Africa system and run the unit, integration, and system tests, and the two case scenarios on the physical robot and the robot simulator. This objective will be achieved by documenting the installation of all software components on an ongoing basis, as a living document, to ensure it reflects the current capabilities of the system. The outcome of this task is described in Deliverable D3.3. Official versions will be produced every six months.

### **Task 3.4: System Integration and Quality Assurance Manual (M6–M9)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to write a manual specifying the procedures to be followed when developing software in the project, submitting it for integration into the current system release, the acceptance unit tests, and the follow-up action required if a module does not pass an acceptance unit test. It identifies the processes that are used to ensure that all software included in the system release adheres to the standards set out in Deliverable D3.2 and follows the related guidelines. This objective will be achieved by adapting and adopting standards using in previous research projects RobotCub and DREAM. The outcome of this task is described in Deliverable D3.4.

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<sup>4</sup><http://www.robotcub.org/>

<sup>5</sup><https://dream2020.github.io/DREAM/>

## Description of Work (continued)

### **Task 3.5: System Integration and Quality Assurance (M10–M36)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to incorporate software submitted for integration in the current version of the CSSR4Africa system. This objective will be achieved by running the accompanying unit tests and subjecting the submitted software to integration tests. If the passes these test, it will then be integrated into the current version. In this way, the software is subjected to strict quality assured. This process will be carried out both on demand, as software is submitted for integration by those responsible for the work in work packages WP4 and WP5, and as required by check-points defined by the project milestones. The task uses the outcome of Task 3.4 as documented in Deliverable D3.4. The outcome of this task is described in Deliverable D3.5.

### **Task 3.6: Use Case Feedback (M25–M27)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to update the system architecture based on feedback from the use case evaluations. This objective will be achieved by identifying any adjustments that are necessary to improve the acceptability, performance, and cultural sensitivity of the use cases. The task uses the outcomes of Task 6.2, as documented in Deliverable D6.2, The outcome of this task is summarized in Deliverable D3.46 and incorporated in revised versions of Deliverables D3.1.

## List of Deliverables

Number	Deliverable Title	Lead Partner	Delivery Month
D3.1	System Architecture Design		M7, M30
D3.2	Software Engineering Standards Manual		M3
D3.3	Software Installation Manual		M6, ..., M36
D3.4	System Integration and Quality Assurance Manual		M9
D3.5	System Integration and Quality Assurance		M12, M24, M36
D3.6	Use Case Feedback		M27

## Description of Deliverables

### **D3.1 System Architecture Design**

*Deliverable type: report.*

This deliverable represents the outcome of Task 3.1. It specifies the CSSR4Africa system architecture in detail, identifying the component subsystems, the modules comprising each subsystem, and the information exchanged between subsystems and modules, including a specification of the data that are input to each module, the data that are output from each module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through ROS topics, services, or actions. Specifically, the deliverable provides the functional specification of the two subsystems to be developed in work package WP4 Robot Sensing (Sensing and Analysis, and Detection of Interaction Events) and the four subsystems to be developed in work package WP5 Robot Behaviours (Animate Behavior, Attention, Interaction Manager, and Gesture, Speech, & Navigation). All data will be specified by both information content and representation.

### **D3.2 Software Engineering Standards Manual**

*Deliverable type: report.*

This deliverable represents the outcome of Task 3.2. It is a manual of software engineering standards comprising five parts, as follows.

1. Module and subsystem specification addressing, e.g., requirements model & use cases, computational model, functional model & functional decomposition, data model, process flow models, behavioural model, class and class-hierarchy definition, object-relationship model, object-behaviour model. ris
2. Module design addressing, e.g., data representation and data-structure definition, algorithm realization (calling sequence, API, method invocation), messaging protocols, control mechanisms (task management, HCI management).
3. Implementation, addressing coding guidelines and internal documentation (comment) guidelines.
4. Testing procedures, addressing, e.g., unit and regression testing, backward compatibility.
5. Documentation, specifically external documentation such as reference manuals, user manuals, configuration, and test procedures.

## Description of Deliverables (continued)

### **D3.3 Software Installation Manual**

*Deliverable type: report.*

This deliverable represents the outcome of Task 3.3. It documents the process for the installation and execution of the software required to instantiate all or part of the CSSR4Africa system and run the unit, integration, and system tests, and the two case scenarios on the physical robot and the robot simulator. It will be created as a living document to ensure it reflects the current capabilities of the system. Official versions will be produced every six months.

### **D3.4 System Integration and Quality Assurance Manual**

*Deliverable type: report.*

This deliverable represents the outcome of Task 3.4. It is a manual specifying the procedures to be followed when developing software in the project, submitting it for integration into the current system release, the acceptance unit tests, and the follow-up action required if a module does not pass an acceptance unit test. It identifies the processes that are used to ensure that all software included in the system release adheres to the standards set out in Deliverable D3.2 and follows the related guidelines.

### **D3.5 System Integration and Quality Assurance**

*Deliverable type: software, report.*

This deliverable represents the outcome of Task 3.5. It comprises the functional integrated software at different stages of the system development. In addition to functional code, the deliverable will include a report on the results of the integration tests. The deliverable will be issued annually over the duration of the project. The final version will present the final system test and a test report, along with a system user manual and a system reference manual.

### **D3.6 Use Case Feedback**

*Deliverable type: report.*

This deliverable represents the outcome of Task 3.6. It documents any adjustments that need to be made to the system architecture based on the evaluation of the two use cases in work package WP6.



Work Package Number	4
Work Package Title	Robot Sensing

## Objectives

1. Develop a suite of unit tests to verify that all sensors are functioning correctly and that the sensor data can be accessed using ROS.
2. Identify and implement algorithms that will detect and localize people, including their face and eyes, localize sounds, and localize the robot in a world frame of reference.
3. Detect interaction events on the robot's tablet PC.
4. Detect speech events and perform automated speech recognition.

## Description of Work

### Task 4.1: Sensor Tests (M1–M3)

*Lead Partner:*

*Participating Partner:*

The objective of this task is to write a suite of unit tests, one for each sensor, to verify that sensor data is successfully acquired on each sensor topic. A subset of the unit tests can be selected, and those that are selected can be run in sequence or in parallel.

This objective will be achieved by creating a list of sensors and the associated topics used by the physical Pepper robot and the Pepper robot simulator, writing a suite of unit tests that will verify the operation of each sensor on both the physical Pepper and the simulator, writing a unit test scheduling program that will use an external configuration file to identify the tests to be run, the manner in which they are to be run (in sequence or in parallel), and the platform on which they are to be run (the physical robot or the simulator). The software development process for each unit test and the scheduling program will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The anticipated outputs of each of these phases are detailed in Deliverable D4.1.

### Task 4.2: Sensing & Analysis (M1–M9)

*Lead Partner:*

*Participating Partner:*

The sensing and analysis task is concerned with analyzing sensor data to detect and localize interaction partners with respect to the robot, and localize the robot with respect its environment. Combined with the cultural knowledge, this information will enable the robot to pay attention to people and interact with them in a culturally sensitive manner by respecting social and cultural norms for proxemics and eye contact. It also supports robot navigation and deictic gestures by the robot to objects in the robot's environment. There are four subtasks. Three focus on the interaction partners and are concerned with detecting and localizing (i) people, (ii) faces and eyes, (iii) sounds, e.g., voices. A fourth subtask is concerned with localizing the robot in the world frame of reference. There is a deliverable for each of the subtasks, rather than a single deliverable for the task overall.

## Description of Work (continued)

### **Task 4.2.1: Person Detection and Localization (M1–M6)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to develop a software module to detect and localize people in the robot's field of view. If a person is detected, her or his position will be determined both in an image frame of reference and in the robot's Cartesian head frame of reference. If needed, the location of the person in a world frame of reference can be computed based on the pose of the robot head with respect to the robot base (determined from the robot kinematic model and the knee pitch, hip pitch, hip roll, head pitch, and head yaw angles) and the pose of the robot base in the world frame of reference (determined in Task 4.2.4). Knowledge of the position of the detected person in either the robot's base frame of reference or the world frame of reference is needed if the robot is required to navigate with respect to the person, e.g., when approaching them or maintaining a respectful distance from them.

Note that this module computes the person's position only, not their pose, i.e., position and orientation. In addition, the region that the person occupies in the image will also be determined by computing the bounding box surrounding the person. This bounding box will be drawn on an output image. If more than one person is present in the robot's field of view, all of them should be detected and localized.

To ensure coherence in detection and localization over time, each detected person should be labelled in the image (e.g., "Person 1") and the same label should be assigned to that person in subsequent images. The label and the bounding box should be colour-coded, assigning different colours to different people, and the same colour is to be given person in each image in a sequence of images. If that person is no longer detected in an image, then that label should not be reused. If that person reappears in a subsequent image, she or he will be given a new label. As such, this module is only concerned with consistent detection of people over time, not recognition of previously detected people. It is assumed that people don't change between images. Each detection is to be assigned a confidence value between 0 and 1 indicating likelihood that the detection is not a false positive. The camera to be used for image acquisition and the depth sensor to be used for 3D localization will be specified in a module configuration file..

The task objective will be achieved by first conducting a review of person detection and localization algorithms, focussing on standard approaches. Three candidate approaches, such as Histogram of Oriented Gradients (HOG), Region-based Convolutional Neural Networks (R-CNN), and deep learning-based models such as YOLO (You Look Only Once), will be implemented for comparison, the best of which (in terms of minimizing false reject and false accept errors) will be selected for use in the project. For localization in the robot's Cartesian head frame of reference, the depth image provided by the RGB-D camera depth sensor will be fused with the visual image (in the case that the visual image is acquired with the forward looking camera, rather than the RGB-D camera). After camera calibration (performed in Task 4.2.5), the camera model will be used with the inverse perspective transformation, along with the depth image, to compute the location of the person in the robot's head frame of reference, and, using the robot kinematic model and the knee pitch, hip pitch, hip roll, and head pitch, and head yaw joint angles, in the robot's base frame of reference. The software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The outputs of each of these phases are detailed in Deliverable D4.2.1.

## Description of Work (continued)

### **Task 4.2.2: Face & Eye Detection and Localization (M1–M6)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to develop a software module to detect and localize the faces and eyes of people in the robot’s field of view. If a face is detected, its position will be determined both an image frame of reference and the robot’s Cartesian head frame of reference. In addition, the region that the face occupies in the image will also be determined by computing the bounding box surrounding the face. This bounding box will be drawn on an output image. If more than one face is present in the robot’s field of view, then all of them should be detected and localized. To ensure coherence in detection and localization over time, each detected face should be labelled (e.g., “Face 1”) and the same label should be assigned to that face in subsequent images. The label and the bounding box should be colour-coded, assigning different colours to different people, and the same colour to a given person in each image in a sequence of images. If that face is no longer detected in an image, then that label should not be reused. If that face reappears in a subsequent image, it will be given a new label. As such, this module is only concerned with consistent detection of faces over time, not recognition of previously detected faces, and it is assumed that faces don’t change between images. Each detection is to be assigned a confidence value between 0 and 1 indicating likelihood that the detection is not a false positive. The camera to be used for image acquisition will be specified in a module configuration file, as will a directive to use the physical robot or the simulator.

This objective will be achieved by utilizing the function for face and eye detection in OpenCV library which uses Haar features and boosted classification techniques. The software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The outputs of each of these phases are detailed in Deliverable D4.2.2.

The task uses the outcome of Task 4.2.1 as documented in Deliverable D4.2.1. Specifically, it uses the output of the personDetector module, i.e., a list of detected persons and their locations and bounding boxes as an optional input. These bounding boxes can be used to define regions of interest in order to restrict the search for the eyes (i.e., at the top of the person bounding boxes).

## Description of Work (continued)

### **Task 4.2.3: Sound Detection and Localization (M1–M6)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to develop a software module to detect and identify the direction of arrival of a conspicuous sound within the robot's hearing range. The direction will be limited to the azimuth (i.e., horizontal) plane. This will allow the robot to direct its gaze in the direction of the sound. If a sound is detected, its angle of arrival will be determined in the robot's Cartesian head frame of reference. The audio signal of the detected sound, from onset of the sound to offset of the sound, will be captured for output. A directive to use the physical robot or the simulator will be specified in a module configuration file, along with the microphones to be used to acquire the audio signal.

This objective will be achieved by computing the interaural time delay (ITD) between the arrival of the sound at the robot's microphones on the top of the robot's head. Other techniques will also be investigated. The module will be tuned to detect human voices rather than ambient sounds or background noise by using signal processing techniques such as band-pass filtering and noise reduction. The software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The outputs of each of these phases are detailed in Deliverable D4.2.3.

### **Task 4.2.4: Robot Localization (M1–M9)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to develop a software module to determine the pose (position and orientation) of the robot in a Cartesian world frame of reference.

This objective will be achieved by a combination of relative position estimation and absolute position estimation. For relative position estimation, both odometry and the use of the robot's inertial management unit will be investigated. For absolute position estimation, we will investigate triangulation using three landmarks, without distance to the landmarks, and triangulation using two landmarks, with distance to the landmarks based on data acquired using the robot's RGB-D camera. This will require the development of functionality for landmark recognition. For this, we will investigate the use of SIFT (Scale Invariant Feature Transform) and YOLO (You Look Only Once). This task also requires the existence of a map of the environment. For this, the output of Task 5.5.3 Environment Map Generation, encapsulated in Deliverable D5.5.3, will be used. To estimate the orientation of the robot, we will ignore adjustments of body posture through rotation about the x and y axes, and we will restrict estimation to rotation about the robot's z axis in the base frame of reference, i.e., rotation about the z axis. This rotation angle can be recovered by determining the direction given by the line of sight from the robot to one of the landmarks, and adjusting for any rotation about the z axis of the robot's head frame of reference with respect to the base frame of reference. The software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The outputs of each of these phases are detailed in Deliverable D4.2.1. The performance of the module will be compared to the localization performance of the SLAM (Simultaneous Localization and Mapping) module that will be developed in Task 5.5.3.

## Description of Work (continued)

### **Task 4.2.5: Camera Calibration (M3–M4)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to develop a software module to determine the  $3 \times 4$  camera model matrix for the robot's top forward facing camera and depth RGB-D camera. The camera model parameters can then be used to compute the inverse perspective transformation which, in turn, can be used to compute the 3D coordinates of an image point, provided the distance to that point is known (e.g., using the robot's depth sensor). The robot does not have binocular cameras so using two camera models, and two inverse perspective transformations, to compute the 3D coordinates of an image point is not an option.

This objective will be achieved by extracting the 2D image control point coordinates from two or more images of a standard checkerboard calibration grid, computing the camera model based on the corresponding 3D world coordinates. The 3D coordinates of the calibration grid will be determined empirically, by placing it at a known position and orientation with respect to the robot head, and computing the coordinates from the spacing of the grid pattern and the grid pose. Thus, the 3D coordinates that are computed using the inverse perspective transformation are defined with respect to the robot head frame of reference.

Knowing the pose of the robot base with respect to the world frame of reference from the robot localization module (Deliverable D4.2.4), and knowing the pose of the robot head with respect to the robot base from the robot kinematic model and the knee pitch, hip pitch, hip roll, head pitch, and head yaw angles, the coordinates of this point the world frame of reference can be determined.

## Description of Work (continued)

### **Task 4.3: Detection of Interaction Events (M4–M15)**

*Lead Partner:*

*Participating Partner:*

Detection of interaction events is a fundamental task that enables robots to perceive and interpret actions exhibited by humans. This capability empowers robots to understand and respond appropriately to their environment and interact with people. Since the development of capabilities for such natural interaction would require much more effort than is feasible in a project the size of CSSR4Africa, we restrict interaction events to simple requests using the tablet PC on the robot (Task 4.3.1). The exact functionality of events depends on the scenario requirements that will be identified in Task 2.1 Use Case Scenario Definition and, in particular, in Task 2.3 Visitor Behavior Specification. In anticipation of more natural interaction in the future, we include an additional task to address automated speech recognition for Kinyarwanda speakers.

#### **Task 4.3.1: Tablet PC Event (M4–M9)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to develop a software module that implements the state transition diagram, developed in Task 2.3 and documented in Deliverable D2.3, capturing the visitor interactions with the robot’s tablet PC.

This objective will be achieved by developing an Android touch screen menu display and option selection application. The menu of options will be driven by the requirements documented in Deliverable D2.3 Visitor Behavior Specification. The selected option will be used in the interaction manager subsystem to trigger the appropriate response by the robot. The module software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The anticipated outputs of each of these phases are detailed in Deliverable D4.3.1.

#### **Task 4.3.2: Speech Event (M4–M15)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to train, test, and deploy a speech-to-text model on the Pepper robot for detecting utterances made by an interaction partner in the language of Kinyarwanda and transcribing them into written text.

This objective will be achieved by analysing an audio signal of a sound detected by the module developed in Task 4.2.3 Sound Detection and Localization. Specifically, it will input the audio signal into a deep neural network that has been trained on a Kinyarwanda data set. The output of this network is the transcribed text. The module software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The anticipated outputs of each of these phases are detailed in Deliverable D4.3.2.

## List of Deliverables

Number	Deliverable Title	Lead Partner	Delivery Month
D4.1	Sensor Unit Tests		M3
D4.2.1	Person Detection and Localization		M3
D4.2.2	Face & Eye Detection and Localization		M3
D4.2.3	Sound Detection and Localization		M3
D4.2.4	Robot Localization		M6
D4.2.5	Camera Calibration		M4
D4.3.1	Tablet PC Event		M6
D4.3.2	Speech Event		M9

## Description of Deliverables

### D4.1 Sensor Tests

*Deliverable type: software and report*

This deliverable represents the outcome of Task 4.1. It comprises the documented software required to build and launch a module implemented as a single ROS node that encapsulates a suite of unit tests to verify that sensor data is successfully acquired on each sensor topic. The ROS node will be named **sensorTest**.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in the task description, identifying gaps and misalignments with actual needs.

The module specification section will define the functional characteristics, as follows. The sensors to be tested are to be identified by reading an associated input file that contains a list of the sensors that are to be tested. The sensor names should be the same as those used in the Pepper documentation. The input data file will be named **sensorTestInput.txt**.

The names of the topics to be used for each sensor will be read from a data file comprising a sequence of key-value pairs. The key is the name of the sensor. The value is the topic name. There will be two data files, one for the physical robot and another for the simulator.

The operation of the unit test module is determined by the contents of a configuration file that contains a list of key-value pairs. One key-value pair will specify the platform on which the tests are to be run, i.e., the physical Pepper robot or the Pepper simulator (e.g., **platform robot | platform simulator**). One key-value pair will specify the mode in which the unit tests should be run: in sequence or in parallel (e.g., **mode sequential | mode parallel**). One key-value pair will specify the filename of the file in which the physical Pepper robot sensor and actuator topic names are stored (e.g., **robotTopics pepperTopics.txt**). One key-value pair will specify the filename of the file in which the simulator sensor and actuator topic names are stored (e.g., **simulatorTopics simulatorTopics.txt**). The configuration file will be named **sensorTestConfiguration.txt**.

## Description of Deliverables (continued)

The results of each test should be written to an output file. Tests should also show the data acquired from the sensor in an appropriate manner, e.g., by displaying the images acquired from a camera or playing the sounds on a loudspeaker. The output file will be named `sensorTestOutput.txt`.

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through files, or ROS subscribers, services, or actions. In addition, it will include the specification of a driver to source test input data, and a specification of stubs to sink test output data. Based on the module specification in the task description, it is planned that the interface of this module will use both the physical robot and the simulator as drivers to generate test data. It is planned to identify appropriate stub programs to sink the output data and visualise the acquired data.

The module design section will specify appropriate data structures that will be used to represent and store the acquired sensor data.

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

The unit testing section will document the results of these using this `sensorTest` module.

Finally, a user manual will be included in the deliverable, explaining how to invoke, provide input to, and configure the `sensorTest` module.



## Description of Deliverables (continued)

### D4.2.1 Person Detection and Localization

*Deliverable type: software and report*

This deliverable represents the outcome of Task 4.2.1. It comprises the documented software required to build and launch a module implemented as a single ROS node to detect and determine the location of people in Pepper’s field of view. The ROS node will be named `personDetection`.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in the task description, identifying gaps and misalignments with actual needs.

The module specification section will define the functional characteristics, as follows.

This module will detect the presence of people in the robot’s field of view and compute their position in an image frame of reference and in the robot’s head Cartesian frame of reference. In addition, the region that the person occupies in the image will also be determined by computing the bounding box surrounding the person. If more than one person is present in the robot’s field of view, then all of them should be detected and localized. To ensure coherence in detection and localization over time, each detected person should be labelled (e.g., “Person 1”) and the same label should be assigned to that person in subsequent images. The label and the bounding box should be colour-coded, assigning different colours to different people, and the same colour to a given person in each image in a sequence of images. If that person is no longer detected in an image, then that label should not be reused. If that person reappears in a subsequent image, she or he will be given a new label.

The input will take the form of an RGB image from one of the robot’s cameras and a depth image from one of the robot’s depth sensors.

The output will take the form of an RGB image and a depth image, with bounding boxes drawn around each detected person, and an array of records, one record for each person detected. The components of a record are the 2D image coordinates denoting the centroid of the bounding box, the width and height of the bounding box, a confidence value between 0 and 1 indicating likelihood that the detection is not a false positive, and the 3D coordinates that define the point that corresponds to the centroid of the bounding box surrounding the person in the image. The RGB image will be published on a topic named `personDetectionRGBImage`. The depth image will be published on a topic named `personDetectionDepthImage`. The array of records will be published on a topic named `personDetectionData`.

The names of the topics to be used for each sensor will be read from a data file comprising a sequence of key-value pairs. The key is the name of the sensor. The value is the topic name.

## Description of Deliverables (continued)

The operation of the module will be determined by parameters provided in a configuration file that contains a list of key-value pairs. One key-value pair will specify the RGB camera to be used (e.g., `camera topCamera | camera depthCamera`). One key-value pair will specify the filename of the file in which the physical Pepper robot sensor and actuator topic names are stored (e.g., `robotTopics pepperTopics.txt`). The configuration file will be named `person-DetectionConfiguration.txt`.

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through ROS topics, services, or actions. In addition, it will include the specification of a driver to source test input data, and a specification of stub to sink test output data. Based on the module specification, it is planned that the interface of this module will use the physical robot as the primary driver to generate test data. Furthermore, it is planned to develop a driver to generate test data by acquiring RGB images from a USB camera or a USB RGB-D camera. This driver will publish the data on the same topics as those used by the physical robot and the simulator. It is planned develop an OpenCV stub module to display the RGB image and write the 2D location data to the screen.

The module design section will specify selected algorithms and data structures, and develop a unit test plan. It is planned to use the function for face and eye detection in OpenCV library which uses Haar features and boosted classification techniques.

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

The unit testing section will present the unit tests. At least two types of unit test will be delivered: (i) verification against module specification, and (ii) validation against requirements definition. An evaluation unit test to determine the robustness of the approach to partial occlusion of the person and different lighting conditions. A test report will document the results of these tests.

In addition, a user manual will be included in the deliverable.

## Description of Deliverables (continued)

### D4.2.2 Face & Eye Detection and Localization

*Deliverable type: software and report*

This deliverable represents the outcome of Task 4.2.2. It comprises the documented software required to build and launch a module implemented as a single ROS node to detect and determine the location of faces and eyes in Pepper’s field of view. The ROS node will be named `faceDetection`.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in the task description, identifying gaps and misalignments with actual needs.

The module specification section will define the functional characteristics, as follows. The module will detect the presence of faces of people in the robot’s field of view and compute their position, and the position of the eyes, in an image frame of reference. In addition, the region that the face occupies in the image will also be determined by computing the bounding box surrounding the face. If more than one face is present in the robot’s field of view, then all of them should be detected and localized. To ensure coherence in detection and localization over time, each face person should be labelled (e.g., “Face 1”) and the same label should be assigned to that face in subsequent images. The label and the bounding box should be colour-coded, assigning different colours to different people, and the same colour to a given person in each image in a sequence of images. If that face is no longer detected in an image, then that label should not be reused. If that face reappears in a subsequent image, it will be given a new label.

The input will take the form of an RGB image from one of the robot’s cameras. An optional input is the output of the `personDetector` module, i.e., a list of detected persons and their locations and bounding boxes. These bounding boxes can be used to define regions of interest in order to restrict the search for the eyes (i.e., at the top of the person bounding boxes).

The output will take the form of an RGB image, with bounding boxes drawn around each detected face and an array of records, one record for each face detected. The components of a record are the 2D image coordinates denoting the centroid of the face bounding box, the width and height of the bounding box, a confidence value between 0 and 1 indicating likelihood that the detection is not a false positive, and the 2D image coordinates of each eye. The image will be published on a topic named `faceDetectionImage`. The array of records will be published on a topic named `faceDetectionData`.

The names of the topics to be used for each sensor will be read from a data file comprising a sequence of key-value pairs. The key is the name of the sensor. The value is the topic name. There will be two data files, one for the physical robot and another for the simulator.

## Description of Deliverables (continued)

The operation of the module will be determined by parameters provided in a configuration file that contains a list of key-value pairs. One key-value pair will specify the platform on which the tests are to be run, i.e., the physical Pepper robot or the Pepper simulator (e.g., platform robot | platform simulator). One key-value pair will specify the RGB camera to be used (e.g., camera topCamera | camera depthCamera). One key-value pair will specify the filename of the file in which the physical Pepper robot sensor and actuator topic names are stored (e.g., robotTopics pepperTopics.txt). One key-value pair will specify the filename of the file in which the simulator sensor and actuator topic names are stored (e.g., simulatorTopics simulatorTopics.txt). The configuration file will be named faceDetectionConfiguration.txt.

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through ROS topics, services, or actions. In addition, it will include the specification of a driver to source test input data, and a specification of stub to sink test output data. Based on the module specification, it is planned that the interface of this module will use the physical robot as the primary driver to generate test data. Furthermore, it is planned to develop a driver to generate test data by acquiring RGB images from a USB camera or a USB RGB-D camera. This driver will publish the data on the same topics as those used by the physical robot and the simulator. It is planned develop an OpenCV stub module to display the RGB image and write the 2D image location data to the screen.

The module design section will specify selected algorithms and data structures, and develop a unit test plan. It is planned to utilize the function for face and eye detection in OpenCV library which uses Haar features and boosted classification techniques.

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

The unit testing section will present the unit tests. At least two types of unit test will be delivered: (i) verification against module specification, and (ii) validation against requirements definition. An evaluation unit test to determine the robustness of the approach to partial occlusion of the face and different lighting conditions. A test report will document the results of these tests.

In addition, a user manual will be included in the deliverable.

## Description of Deliverables (continued)

### D4.2.3 Sound Detection and Localization

*Deliverable type: software and report*

This deliverable represents the outcome of Task 4.2.3. It comprises the documented software required to build and launch a module implemented as a single ROS node to detect and determine the direction of arrival of a conspicuous sound within the robot's hearing range. The ROS node will be named `soundDetection`.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in the task description, identifying gaps and misalignments with actual needs.

The module specification section will define the functional characteristics, as follows. The module will detect and determine the direction of arrival of a conspicuous sound within the robot's hearing range, and output the direction angle and the audio signal of the detected sound, from onset of the sound to offset of the sound. The module should be robust enough to operate in challenging acoustic conditions, e.g., in rooms with background noise or reverberation. Localization will be limited to the azimuth (i.e., horizontal) plane. If a sound is detected, its direction of arrival will be determined in the robot's Cartesian head frame of reference. The module will be tuned to detect human voices rather than ambient sounds or background noise by using signal processing techniques such as band-pass filtering and noise reduction. While the interaural time delay (ITD) between the arrival of the sound at the robot's microphones on the top of the robot's head is planned as the initial approach to be used to compute the direction of arrival of the sound, other techniques will also be investigated and evaluated, as required.

The input will take the form of a multichannel audio signal acquired using the robot's four microphones.

The output will be the angle of arrival of the sound in the robot's Cartesian head frame of reference, specified in degrees, and published on a topic named `soundDetectionDirection`. In addition, the left channel of the audio signal that is captured will be published on a topic named `soundDetectionSignal`.

The names of the topics to be used for each sensor will be read from a data file comprising a sequence of key-value pairs. The key is the name of the sensor. The value is the topic name. There will be two data files, one for the physical robot and another for the simulator.

## Description of Deliverables (continued)

The operation of the module will be determined by parameters provided in a configuration file that contains a list of key-value pairs. One key-value pair will specify the platform on which the tests are to be run, i.e., the physical Pepper robot or the Pepper simulator (e.g., `platform robot | platform simulator`). One key-value pair will specify the localization technique to be used (e.g., `algorithm ITD`). One key-value pair will specify the low cutoff frequency in the band-pass filter in hertz, e.g., `lowFrequencyCutoff 100`). One key-value pair will specify the high cutoff frequency in the band-pass filter in hertz, e.g., `highFrequencyCutoff 15000`). One key-value pair will specify the threshold energy of the audio signal that qualifies it as a conspicuous sound. e.g., `thresholdEnergy 200`). One key-value pair will specify the filename of the file in which the physical Pepper robot sensor and actuator topic names are stored (e.g., `robotTopics pepperTopics.txt`). One key-value pair will identify the filename of the file in which the simulator sensor and actuator topic names are stored (e.g., `simulatorTopics simulatorTopics.txt`). The configuration file will be named `soundDetectionConfiguration.txt`.

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through ROS topics, services, or actions. In addition, it will include the specification of a driver to source test input data, and a specification of stub to sink test output data. Based on the module specification, it is planned that the interface of this module will use the physical robot as the primary driver to generate test data. Furthermore, it is planned to develop a driver to generate test data either by acquiring audio signals from the stereo microphone input on the PC or from a data file. This driver will publish the data on the same topics as those used by the physical robot and the simulator. It is planned to develop a stub module to subscribe to the topic on which the direction of arrival is published, and write the angle value to the screen.

The module design section will specify selected algorithms and data structures, and develop a unit test plan. It is planned to consider focus initially on interaural time difference (ITD) but other techniques will also be investigated and evaluated, as required.

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

The unit testing section will present the unit tests. At least two types of unit test will be delivered: (i) verification against module specification, and (ii) validation against requirements definition. An evaluation unit test to determine the robustness of the approach to different acoustic environments and conditions, e.g., rooms with reverberation, background noise such as air conditioning, and the presence of background chatter. A test report will document the results of these tests.

In addition, a user manual will be included in the deliverable.

## Description of Deliverables (continued)

### D4.2.4 Robot Localization

*Deliverable type: software and report*

This deliverable represents the outcome of Task 4.2.4. It comprises the documented software required to build and launch a module implemented as a single ROS node to determine the pose (position and orientation) of the robot in a Cartesian world frame of reference. The ROS node will be named `robotLocalization`.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in the task description, identifying gaps and misalignments with actual needs.

The module specification section will define the functional characteristics, as follows. This module will compute the pose of the robot in the world frame of reference. It will do this continuously, in real time, by updating the current pose based on relative pose estimation, using either odometry or the robot's inertial management unit IMU (or a combination of both). Since pose estimation errors using relative techniques grow with time, the module will periodically reset its pose estimate using absolute pose estimation. Position estimation will be accomplished by triangulation, using either three landmarks without distance to the landmarks, or triangulation using two landmarks with distance to the landmarks based on data acquired using the robot's RGB-D camera (or a combination of both). Landmark recognition will be accomplished either using SIFT (Scale Invariant Feature Transform) or YOLO (You Look Only Once) real-time object detection. The position of the landmarks will be extracted from a map of the environment. This map will be produced in Task 5.5.3 Environment Map Generation. The orientation of the robot will be computed only for its rotation about the z axis; adjustments of body posture through rotation about the x and y axes will be ignored. This rotation angle will be recovered by determining the direction given by the line of sight from the robot to one of the landmarks, and adjusting for any rotation about the z axis of the robot's head frame of reference with respect to the base frame of reference.

For relative pose estimation, the input will be the odometry data published by the robot and data from the robot's accelerometer and gyrometer. For absolute pose estimation, the input will take the form of an RGB image from one of the robot's cameras and a depth image from one of the robot's depth sensors. Input will also be acquired from the encoder on the head yaw actuator, i.e., the joint responsible for rotation in the azimuth (horizontal) plane.

The output will take the form of an RGB image, with bounding boxes drawn around each detected landmark, a depth image, again with bounding boxes drawn around each detected landmark, and a record with the 2D pose information: x and y coordinates and rotation about the z axis. The RGB image will be published on a topic named `robotLocalizationRGBImage`. The depth image will be published on a topic named `robotLocalizationDepthImage`. The record will be published on a topic named `robotLocalizationPoseData`.

The names of the topics to be used for each sensor will be read from a data file comprising a sequence of key-value pairs. The key is the name of the sensor. The value is the topic name. There will be two data files, one for the physical robot and another for the simulator.

## Description of Deliverables (continued)

The operation of the module will be determined by parameters provided in a configuration file that contains a list of key-value pairs. One key-value pair will specify the platform on which the tests are to be run, i.e., the physical Pepper robot or the Pepper simulator (e.g., `platform robot | platform simulator`). One key-value pair will specify the RGB camera to be use (e.g., `camera topCamera | camera depthCamera`). One key-value pair will specify the distance that can be travelled in centimetres before the relative pose estimate is reset using the absolute pose estimate (e.g., `resetInterval 300`). One key-value pair will specify the filename of the file in which the physical Pepper robot sensor and actuator topic names are stored (e.g., `robotTopics pepperTopics.txt`). One key-value pair will specify the filename of the file in which the simulator sensor and actuator topic names are stored (e.g., `simulatorTopics simulatorTopics.txt`). The configuration file will be named `robotLocalizationConfiguration.txt`.

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through ROS topics, services, or actions. In addition, it will include the specification of a driver to source test input data, and a specification of stub to sink test output data. Based on the module specification, it is planned that the interface of this module will use the physical robot as the primary driver to generate test data. Furthermore, it is planned to develop a driver to generate test data by acquiring RGB images from a USB camera or a USB RGB-D camera, and acquiring depth images from a USB RGB-D camera. This driver will also publish synthetic odometry data and synthetic IMU data. It is planned develop an OpenCV stub module to display the RGB and depth images and write the pose data to the screen.

The module design section will specify selected algorithms and data structures, and develop a unit test plan. It is planned to consider several options, including SIFT and YOLO for landmark recognition, two-point and three-point triangulation for absolute position estimation.

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

The unit testing section will present the unit tests. At least two types of unit test will be delivered: (i) verification against module specification, and (ii) validation against requirements definition. An evaluation unit test will be delivered to determine the robustness of the approach to partial occlusion of the landmarks and different lighting conditions. This evaluation test will also include a comparison of the performance of the module with the localization performance of the SLAM (Simultaneous Localization and Mapping) module in Deliverable D5.5.3 Environment Map Generation. A test report will document the results of these tests.

In addition, a user manual will be included in the deliverable.



## Description of Deliverables (continued)

### D4.2.5 Camera Calibration

*Deliverable type: software and report*

This deliverable represents the outcome of Task 4.2.5. It comprises the documented software required to build and launch a module implemented as a single ROS node to determine the  $3 \times 4$  camera model matrix for the robot's top forward facing camera and for the depth RGB-D camera. The ROS node will be named `cameraModel`.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in the task description, identifying gaps and misalignments with actual needs.

The module specification section will define the functional characteristics, i.e., the ability to determine the  $3 \times 4$  camera model matrix for the robot's top forward facing camera and for depth RGB-D camera by extracting the 2D image control point coordinates from two or more images of a standard checkerboard calibration grid and computing the camera model based on the corresponding 3D world coordinates. The 3D coordinates of the calibration grid will be determined empirically, by placing it at a known position and orientation with respect to the robot head, and computing the coordinates from the spacing of the grid pattern and the grid pose. Thus, the 3D coordinates that are computed using the resultant inverse perspective transformation are defined with respect to the robot head frame of reference.

The input will take the form of RGB images from the robot's top camera and the robot's RGB-D depth sensor. In addition, the module will input from file the specification of the camera calibration setup (i.e., calibration grid pattern, spacing, position, and orientation), and the coordinates of the 3-D world control points, either all points or the four extreme corner points, with the remaining points being computed by bilinear interpolation.

The output will be a file containing the twelve floating point elements of the camera model matrix. The module will also output the RGB image with the calibration points graphically identified. The RGB image will be published on a topic named `cameraModelRGBImage`.

The names of the topics to be used for each sensor will be read from a data file comprising a sequence of key-value pairs. The key is the name of the sensor. The value is the topic name. There will be two data files, one for the physical robot and another for the simulator.

## Description of Deliverables (continued)

The operation of the module will be determined by parameters provided in a configuration file that contains a list of key-value pairs. One key-value pair will specify the camera to be calibrated (e.g., `camera topCamera | camera depthCamera`). One key-value pair will specify the number of views of the calibration grid to use in the calibration process (e.g., `numberOfViews 2`). One key-value pair will specify the filename of the .xml file that contains the specification of the camera calibration setup, including the size of the calibration grid, the grid spacing, and the calibration pattern (e.g., `calibrationConfiguration cameraCalibConfig.xml`). One key-value pair will specify the filename of the file that contains the the coordinates of the corresponding 3-D world control points (e.g., `worldControlPoints cameraModelWorldControlPoints.txt`). One key-value pair will specify the filename of the file to which the twelve floating point elements of the camera model matrix are to be written. (e.g., `cameraModel cameraModelCoefficients.txt`). One key-value pair will specify the filename of the file in which the physical Pepper robot sensor and actuator topic names are stored (e.g., `robotTopics pepperTopics.txt`). One key-value pair will specify the filename of the file in which the simulator sensor and actuator topic names are stored (e.g., `simulatorTopics simulatorTopics.txt`). The configuration file will be named `cameraModelConfiguration.txt`.

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through ROS topics, services, or actions. In addition, it will include the specification of a driver to source test input data, and a specification of stub to sink test output data. Based on the module specification, it is planned that the interface of this module will use the physical robot as the primary driver to generate test data. Furthermore, it is planned to develop a driver to generate test data by acquiring RGB images from a USB camera and a USB RGB-D camera, in the case that the RGB camera is being calibrated, or just a USB RGB-D camera, in the case that the RGB-D camera is being calibrated. It is planned develop an OpenCV stub module to display the RGB image and write the computed camera model values to the screen.

The module design section will specify selected algorithms and data structures, and develop a unit test plan. It is planned to compute the camera model by computing a least-square-error solution to an over-determined system of equations derived by associating image control point coordinates, world control point coordinates, and the camera model coefficients.

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

The unit testing section will present the unit tests. One unit test will verify that the camera model can regenerate all the x and y coordinates of the world control points from the coordinates of the image control points and the z values of the world control point. One unit test will allow a user to interactively select an image point in the input RGB image and display the corresponding 3D world coordinates. A test report will document the results of these tests.

In addition, a user manual will be included in the deliverable.

## Description of Deliverables (continued)

### D4.3.1 Tablet PC Event

*Deliverable type: software and report*

This deliverable represents the outcome of Task 4.3.1. It comprises the documented software required to implement the state transition diagram, developed in Task 2.3 and documented in Deliverable D2.3, capturing the visitor interactions with the robot's tablet PC. This application will form the response to a ROS service request by the interaction manager subsystem to display a menu of interaction options that are appropriate in the current context of the scenario, wait for the visitor to select an option, and return the option selected.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in this work plan, identifying gaps and misalignments with actual needs.

The module specification section will specify the functional characteristics, detailing the input to output data transformation, expected input, expected output data, module configuration parameters, and a draft user manual. Functionally, this module will display a menu of options that the user can select. The menu is specified in the ROS service request. The module will block until the user touches the table PC screen, and, depending on the area touched, the module will unblock and respond to the service with the identifier of the selected option. The operation of the module will be determined by parameters provided in a configuration file. These parameters comprise a list of key-value pairs. One key-value pair will specify the filename of the menu data (e.g., `menuDataFile menuData.txt`). The module's application programming interface (API), i.e., the invocation and control of the module, will be documented in a user manual.

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed through ROS services and files. In addition, it will include the specification of a driver to request this service, and display the menu option selected by the visitor with whom the robot is interacting.

The module design section will specify selected algorithm and data structure used to match the screen region to the menu option identifier, and develop a unit test plan.

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

The unit testing section will provide a verification unit test to ensure that the correct menu option identifier is used in the service response. A test report will document the results of these tests.

In addition, a user manual will be included in the deliverable.

## Description of Deliverables (continued)

### D4.3.2 Speech Event

*Deliverable type: software and report*

This deliverable represents the outcome of Task 4.3.2. It comprises the documented software required to build and launch a module implemented as a single ROS node that detects a utterance, represented as an audio signal, spoken by an interaction partner in the Kinyarwanda language and transcribes it into written text.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in this work plan, identifying gaps and misalignments with actual needs.

The module specification section will specify the functional characteristics, detailing the input to output data transformation, expected input data, expected output data, module configuration parameters, and a draft user manual. Functionally, this module first requires that a deep neural network be trained and tested so that it can perform automated speech recognition. This network will subsequently be used to take as input the audio signal of a sound detected by the module developed in Task 4.2.3 Sound Detection and Localization, and produce the corresponding written text. In the case that the spoken utterance cannot be recognized, either because the sound is not a spoken utterance or because it uses vocabulary on when the neural network has not been trained, then the module will flag this by producing a text that reads “Error: speech not recognized”.

The input will take the form of an audio signal that is captured in the `soundDetection` module, published on a topic named `soundDetectionSignal`.

The output will take the form of a record containing a string representing the message in the spoken audio signal. This will be published on a topic named `speechEventText`.

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through ROS topics, services, or actions. In addition, it will include the specification of a driver to source test input data, and a specification of stub to sink test output data. Based on the module specification, it is planned that the interface of this module will develop a driver to generate test data based on parameters defined in the driver input file. It is planned to develop a stub to sink the output data and visualise this data, i.e., by writing the transcribed text to the terminal.

The module design section will comprise a complete and comprehensive description of the deep neural network and the training procedure.

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

### **Description of Deliverables (continued)**

The unit testing section will present the unit tests. At least two types of unit test will be delivered: (i) verification against module specification, and (ii) validation against requirements definition. Where feasible, an evaluation unit test against benchmark data or standard metrics will be delivered. A test report will document the results of these tests.

In addition, a user manual will be included in the deliverable.

Work Package Number	5
Work Package Title	Robot Behaviors

## Objectives

1. Develop a suite of unit and system tests to demonstrate that all actuators are functioning correctly and can be controlled using ROS.
2. Develop an animate behaviour subsystem comprising software modules that enable the robot to exhibit life-like characteristics which encourage interaction by the human partner.
3. Develop an attention sub-system comprising software modules that controls the robot's overt attention.
4. Develop an interaction manager subsystem comprising software module that controls robot interaction with a human partner, taking into consideration culturally sensitive behaviors for Africa and the requirements of a use case scenario.
5. Develop a subsystem comprising software modules for robot gestures, speech, and navigation.

## Description of Work

### Task 5.1: Actuator Tests (M1–M3)

*Lead Partner:*

*Participating Partner:*

The objective of this task is to write a suite of unit tests, one for each actuator, to verify that every actuator can be controlled successfully using ROS. A subset of the unit tests can be selected, and those that are selected can be run in sequence or in parallel.

This objective will be achieved by creating a list of actuators and the associated topics used by the physical Pepper robot and the Pepper robot simulator, writing a suite of unit tests that will verify the operation of each sensor on both the physical Pepper and the simulator, writing a unit test scheduling program that will use an external configuration file to identify the tests to be run, the manner in which they are to be run (in sequence or in parallel), and the platform on which they are to be run (the physical robot or the simulator). In the case of joint actuators, the unit test should move each joint to its minimum, maximum, and mid-range position (in that order) at a selected velocity, e.g., 50% of the maximum velocity. In the case of wheel actuators, there will be two unit tests. The first unit test should rotate the robot at a selected positive angular velocity, e.g.,  $90^\circ/\text{s}$ , for a fixed period of time, e.g., one second, and it should then rotate the robot at a selected negative angular velocity, e.g.,  $-90^\circ/\text{s}$ , for a fixed period of time. The second unit test should move the robot at a selected positive linear velocity, e.g.,  $1\text{m}/\text{s}$ , for a fixed period of time, e.g., one second, and it should then move the robot at a selected negative linear velocity, e.g.,  $-1\text{m}/\text{s}$ , for a fixed period of time. These unit tests should work with both the physical robot and the robot simulator.

The software development process for each unit test and the scheduling program will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The anticipated outputs of each of these phases are detailed in Deliverable D5.1.

## Description of Work (continued)

### **Task 5.2: Animate Behavior Subsystem (M4–M9)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to develop a software module to give the robot the appearance of an animate agent by continually making subtle body movements, flexing its hands a little, and rotating its base slightly.

This objective will be achieved by actuating the robot joints periodically in some random pattern, keeping the joint angles close to the default home positions. The extent of the movements should be determined by an external parameter. Since the robot should not make these animate movements when engaged in culturally sensitive social interaction through gestures, speech, or when navigating, the module will not control the relevant actuators directly. Instead, it will send the appropriate control commands to the Gesture, Speech, and Navigation subsystem which can either redirect to them to the robot or not, as appropriate. Note that, from a software architecture perspective, the Attention subsystem may also contribute to the appearance of an animate agent by directing the robot gaze to relevant objects, even when not engaging in social interaction. The software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The anticipated outputs of each of these phases are detailed in Deliverable description D5.2 Animate Behavior Subsystem. The task uses the outcome of Task 5.1 Actuator Tests as documented in Deliverable D5.1.

### **Task 5.3: Attention Subsystem (M4–M12)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to develop a software module to allow the robot to pay attention to salient features in its environment. The primary salient features are those that are associated with social interaction, mainly people's bodies, faces, eyes, and voices. These features will also be the focus of attention when the robot is not interacting, but is merely observing its environment. As such, attention also contributes to the animate behavior of the robot (Task 5.2). Observing the environment also involves scanning the environment for interesting objects. For this, a more general-purpose saliency function is required to complement the social interaction feature saliency function. Furthermore, scanning the environment requires the robot to change its focus of attention after some time and not return directly to the original focus of attention.

This objective will be achieved by generating two saliency maps, one based on social feature and one based on general interesting features. The former will use the output of Task 4.2.2 Face and Eye Detection and Localization and Task 4.2.3 Sound Detection and Localization. Candidates for the latter include the Itti and Koch saliency model of visual attention (Itti et al., 1998; Itti & Koch, 2000, 2001), the model proposed by Rea et al. (2013), the information-theoretic saliency map (Bruce & Tsotsos, 2009), and open source deep neural network saliency models. A single focus of attention will be selected from the saliency map with a winner-take-all process. An habituation process to reduce the salience of the current focus of attention with time, thereby ensuring that attention is fixated on a given point for a limited period. An Inhibition-of-Return (IOR) mechanism will be developed to attenuate the attention value of previous winning locations so that new regions become the focus of attention. Furthermore, attention will also be directed towards conspicuous sounds. Aural attention will have a higher priority than visual attention.

## Description of Work (continued)

The robot's gaze will be adjusted so that the gaze is centred on the focus of attention. This requires the calibration of the x and y offset of the focus of attention in the image to the change in headYaw and headPitch angles, respectively. For simplicity, it will be assumed that there is a linear relationship between these two variables. In the case of aural attention to conspicuous sounds, it requires the calibration of the angle of arrival of the sound with the change in headYaw angle. Fixation on sounds will only control the headYaw angle, i.e., rotation in the horizontal plane about the head's z axis. If the angle of rotation of the headYaw is greater than some given threshold, then after rotating the head to fixate on the focus of attention, the base of the robot and the head will rotate in opposite directions so that the robot continues to gaze at the focus of attention as it realigns its head with its body.

The software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The anticipated outputs of each of these phases are detailed in Deliverable D5.2 Attention. The task uses the output of Task 4.2.2 Face and Eye Detection and Localization and Task 4.2.3 Sound Detection and Localization.

### **Task 5.4: Interaction Manager Subsystem (M4–M18)**

*Lead Partner:*

*Participating Partner:*

The Interaction Manager Subsystem will orchestrate the way the Pepper robot interacts with visitors in the two demonstration scenarios, using culturally sensitive spatial, nonverbal, and speech actions. There are four elements to this task:

1. The development of a cultural knowledge ontology.
2. The population of a knowledge base that adheres to the structure given by the ontology.
3. The definition of a scenario script language that can capture the interactions in different social robotics scenarios, and the two selected use case scenarios, in particular.
4. The specification, design, implementation of an interpreter for the script language that can transform the interactions specified in the use case scenarios into a sequence of culturally sensitive human-robot interactions.

Elements 1 and 2 are addressed in Task 5.4.1, effectively formalizing the knowledge that will have been acquired in work package WP1. Element 2 is addressed in Task 5.4.2 and element 3 is addressed in Task 5.4.3.



## Description of Work (continued)

### **Task 5.4.1: Cultural Knowledge Ontology & Knowledge Base (M4–M9)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to formulate a cultural knowledge ontology and use it to create a knowledge base formalizing the culturally sensitive knowledge that are documented in Deliverables D1.2 African Modes of Social Interaction and D1.3 Africa-centric Design Patterns.

This objective will be achieved by mapping the knowledge in Deliverable D1.2 to the cultural knowledge ontology proposed by Bruno et al. (2019), adapting the ontology and extending it, as necessary, based both on the other ontologies in the literature and the requirements of cultural knowledge in Africa, specifically in South Africa and Rwanda. This will facilitate the development of a structured knowledge base that encapsulates the knowledge captured in Deliverable D1.3. The outcome of this task is described in Deliverable D5.4.1.

### **Task 5.4.2: Scenario Script Language (M4–M12)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to define a language that can be used to capture the interactions in the use case scenarios and enact them using the cultural knowledge ontology and cultural knowledge base.

This objective will be achieved by modelling the use case scenarios with finite state machines (FSM) and mapping these to an associated finite state language and grammar. The task uses the outcome of Task 2.1, documented in Deliverable D2.1, by recruiting the robot and visitor behaviors documented in Deliverables D2.2 and D2.3. It also uses the cultural knowledge ontology and cultural knowledge base developed in Task 5.4.1, encapsulated in Deliverable D5.4.1. The outcome of this task is described in Deliverable D5.4.2.

### **Task 5.4.3: Scenario Script Interpreter (M13–M18)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to develop an interpreter for the scenario script language defined in Deliverable D5.4.2.

This objective will be achieved either by developing a domain specific language (DSL), based on the language grammar, to implement a finite state machine (FSM) model of the interaction, or by adapting an open source implementation of a FSM language interpreter.

## Description of Work (continued)

### **Task 5.5: Expression & Actuation Subsystem (M4–M12)**

*Lead Partner:*

*Participating Partner:*

The Expression and Actuation Subsystem enables the robot to interact with people in a culturally sensitive manner, and navigate its environment while doing so. It also implements the animate behavior actuation when the robot is idle, i.e., when it is not engaged in interaction. It comprises three interaction tasks, one concerned with non-verbal gestural communication, one with speaking to people, and one with navigating the environment, adhering to cultural norms as it moves. The latter has an associated task concerned with creating a map of the environment that the robot has to navigate.

#### **Task 5.5.1: Gesture Execution (M4–M15)**

*Lead Partner:*

*Participating Partner:*

The objective of the Gesture Execution task is to specify, design, implement, and test a ROS module that enables the Pepper robot to execute body and hand gestures. Hand gestures will include deictic, symbolic, and iconic non-verbal gestures. Body gestures will be restricted to bowing and nodding, i.e., lowering and raising gaze.

This objective will be achieved by identifying a way of specifying all five forms of gesture. These specifications will be in joint space, rather than Cartesian space. Some gestures, e.g., iconic and symbolic hand gestures will be specified by learning the required motions either by, recording the joint angles during manual teleoperation, or by demonstration, using an RGB-D depth camera to determine the joint angles of human gestures in a skeletal model of and mapping these to the robot joints. Other gestures, i.e., deictic hand gestures and body gestures, will be specified by gesture parameters, such as the pointing direction for deictic gestures and the degree of inclination for bowing and nodding, and the joint angles will be computed using the kinematic model of the robot head, torso, and arms. For deictic gestures, which require the robot to point at objects in its environment, the pose of the robot in the world frame of reference will also be used.

The software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The anticipated outputs of each of these phases are detailed in Deliverable D5.5.1.

The task uses the outcome of Task 4.2.4 Robot Localization as documented in Deliverable D4.2.4.

## Description of Work (continued)

### **Task 5.5.2: Text to Speech Conversion (M4–M12)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to implement a text to speech facility that will allow the Pepper robot to communicate with humans using spoken language. The primary language of communication will be English. In anticipation of more natural interaction in the future, we will also address text to speech for Kinyarwanda speakers, so that Pepper will be able to use its voice to provide spoken greetings and responses in Kinyarwanda. The possibility of controlling loudness, pitch, and timbre of the speech will be investigated.

This objective will be achieved by investigating the feasibility of using the NAOqi audio utility ALTextToSpeech through a ROS interface. In parallel, we will investigate the development of a speech synthesis engine for Kinyarwanda, possibly leveraging work by Rutunda et al. (2023).

The software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The anticipated outputs of each of these phases are detailed in the associated deliverable description. The outcome of these phases are described in Deliverable D5.5.2.

The task uses the outcome of Task 5.4.3 as documented in Deliverable D5.4.3 Scenario Script Interpreter.

### **Task 5.5.3: Environment Map Generation (M1–M9)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to implement a software module to generate a metric map of the environments that will be used in the two use case scenarios documented in Deliverable D2.1. This map will be used by the Pepper robot when navigating and when making deictic gestures, i.e., when pointing at items of interest to the human in the use case scenario. As such, the map will not only compute the environment workspace space (i.e., the locations that are not occupied by obstacles) but also the locations and identities of objects of interest, as specified in the use case scenarios. Thus the map will comprise both non-symbolic metric data and symbolic semantic data.

This objective will be achieved by pursuing two approaches: (a) map generation from a priori data (i.e., environment CAD data), and (b) map generation using Simultaneous Localization and Mapping (SLAM). Both will generate non-symbolic metric map data that can be visualized as an image, and a list of the locations of labelled objects of interest, interactively selected by a human map builder.

The software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The anticipated outputs of each of these phases are detailed in the associated deliverable description. The outcome of these phases are described in Deliverable D5.5.3.

The task uses the outcome of Task 5.4.3 as documented in Deliverable D5.4.3 Scenario Script Interpreter.

## Description of Work (continued)

### **Task 5.5.4: Robot Navigation (M4–M15) *Lead Partner:***

#### *Participating Partner:*

The objective of this task is to implement a software module to control the locomotion of the Pepper robot so that it can navigate in its environment, in which there are fixed inanimate obstacles and moveable obstacles in the form of humans, from its current position to a target destination along the shortest path. Navigation will be effected by identifying waypoints along the navigation path and the robot will move from waypoint to waypoint.

This objective will be achieved by first augmenting a metric workspace map of the robot's environment, i.e., the outcome of Task 5.5.3), with obstacles corresponding to the location of any humans that have been detected in the robot's field of view. The size of the human obstacle will be determined using culturally sensitive proxemics. This augmented workspace map will then be used to generate a configuration space map (i.e., the positions that robot can actually occupy, taking into consideration the size and shape of its base) that constrains the robot's path from its current location to its target location. The shortest path will then be computed using one of two shortest path algorithms: Dijkstra's algorithm and the A\* algorithm. Waypoints will be identified using one of two candidate techniques: equidistant waypoints and high path curvature waypoints. Locomotion from waypoint to waypoint will be effected using one of two locomotion algorithms, such as Multiple Input Multiple Output (MIMO) and divide and conquer (DnQ).

The software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The anticipated outputs of each of these phases are detailed in the associated deliverable description. The outcome of these phases are described in Deliverable D5.5.3.

The task uses the information produced by the modules in Deliverables D1.2 African Modes of Social Interaction, D2.1 Use Case Scenario Definition, D4.2.1 Person Detection and Localization, D5.4.3 Scenario Script Interpreter, and D5.5.3 Environment Map Generation.

## List of Deliverables

Number	Deliverable Title	Lead Partner	Delivery Month
D5.1	Actuator Tests		M3
D5.2	Animate Behavior Subsystem		M3
D5.3	Attention Subsystem		M6
D5.4.1	Cultural Knowledge Ontology & Knowledge Base		M9
D5.4.2	Scenario Script Language		M12
D5.4.3	Scenario Script Interpreter		M18
D5.5.1	Gesture Execution		M15
D5.5.2	Text to Speech Conversion		M12
D5.5.3	Environment Map Generation		M9
D5.5.4	Robot Navigation		M15

## Description of Deliverables

### D5.1 Actuator Tests

*Deliverable type: software and report*

This deliverable represents the outcome of Task 5.1. It comprises the documented software required to build and launch a module implemented as a single ROS node that encapsulates a suite of unit tests to verify that each actuator can be successfully controlled. The ROS node will be named `actuatorTest`.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in the task description, identifying gaps and misalignments with actual needs.

The module specification section will define the functional characteristics, as follows.

In the case of joint actuators, the unit test will move each joint to its minimum, maximum, and mid-range position (in that order) at a selected velocity, e.g., 50% of the maximum velocity. In the case of wheel actuators, there will be two unit tests. The first unit test will rotate the robot at a selected positive angular velocity, e.g.,  $90^\circ/\text{s}$ , for a fixed period of time, e.g., one second, and it will then rotate the robot at a selected negative angular velocity, e.g.,  $-90^\circ/\text{s}$ , for a fixed period of time. The second unit test will move the robot at a selected positive linear velocity, e.g.,  $1\text{m/s}$ , for a fixed period of time, e.g., one second, and it will then move the robot at a selected negative linear velocity, e.g.,  $-1\text{m/s}$ , for a fixed period of time. These unit tests should work with both the physical robot and the robot simulator.

The names of the topics to be used for each actuator will be read from a data file comprising a sequence of key-value pairs. The key is the name of the actuator. The value is the topic name. There will be two data files, one for the physical robot and another for the simulator.

The actuators to be tested are to be identified by reading an associated input file that contains a list of the actuators that are to be tested. The actuator names should be the same as those used in the Pepper documentation. The input data file will be named `actuatorTestInput.txt`.

## Description of Deliverables (continued)

The operation of the module will be determined by parameters provided in a configuration file that contains a list of key-value pairs. One key-value pair will specify the platform on which the tests are to be run, i.e., the physical Pepper robot or the Pepper simulator (e.g., `platform robot` | `platform simulator`). One key-value pair will specify the mode in which the unit tests should be run: in sequence or in parallel (e.g., `mode sequential` | `mode parallel`). One key-value pair will specify the filename of the file in which the physical Pepper robot sensor and actuator topic names are stored (e.g., `robotTopics pepperTopics.txt`). One key-value pair will specify the filename of the file in which the simulator sensor and actuator topic names are stored (e.g., `simulatorTopics simulatorTopics.txt`). The configuration file will be named `actuatorTestConfiguration.txt`.

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through files, or ROS subscribers, services, or actions. Based on the module specification in the task description, it is planned that the interface of this module will use both the physical robot and the simulator to sink the control data published on the various actuator topics.

The module design section will specify selected message data structures used to represent and store the topic messages required to control the actuators.

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

The unit testing section will document the results of these using this `actuatorTest` module.

Finally, a user manual will be included in the deliverable, explaining how to invoke, provide input to, and configure the `actuatorTest` module.

## Description of Deliverables (continued)

### D5.2 Animate Behavior Subsystem

*Deliverable type: software and report*

This deliverable represents the outcome of Task 5.2. It comprises the documented software required to build and launch a module implemented as a single ROS node that gives the robot the appearance of an animate agent by continually making subtle body movements, flexing its hands a little, and rotating its base slightly. The ROS node will be named `animateBehavior`.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in the task description, identifying gaps and misalignments with actual needs.

The module specification section will define the functional characteristics, i.e., actuating the robot joints periodically in some random pattern, keeping the joint angles close to the default home positions. All the joints, except `headYaw` and `headPitch`, will be actuated, as well as the wheels to effect rotation about the robot's `z` axis but not forward movement along the robot's `x` axis. The `headYaw` and `headPitch` joints will be actuated by the Attention subsystem. The extent of the movements will be determined by an external parameter. Specifically, the range of movement, from which the actual movement will be a random sample, will be specified as a percentage of half the full range of movement. Thus, 50% would mean that the amount of motion would vary randomly between the home value and half the maximum value, assuming the home value is midway between the minimum and maximum values.

The names of the topics to be used for each actuator will be read from a data file comprising a sequence of key-value pairs. The key is the name of the actuator. The value is the topic name. There will be two data files, one for the physical robot and another for the simulator. However, as noted above, the module will not control these actuators directly. Instead, it will publish the control messages on pseudo actuator topics, appending `Animate` to the topic name to differentiate it from the topic that use used to control the actuators. The Gesture, Speech, and Navigation subsystem can then subscribe to these topics and resend the control messages to the actuator topics, depending on whether or not it is engaged in social interaction.

Any of the three types of animate behavior — body movement, hand flex, and rotation — can be selectively invoked. All three will be invoked if none are selectively invoked.

To ensure that the robot does not make these animate movements when engaged in culturally sensitive social interaction through gestures, speech, or when navigating, the module will not control the relevant actuators directly. Instead, it will send the appropriate control commands to the Gesture, Speech, and Navigation subsystem which, can either redirect to them to the robot or not, as appropriate.

The software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The anticipated outputs of each of these phases are detailed in the associated deliverable description (D5.2).

## Description of Deliverables (continued)

The operation of the `animateBehavior` module is determined by the contents of a configuration file that contain a list of key-value pairs. One key-value pair will specify the platform on which the tests are to be run, i.e., the physical Pepper robot or the Pepper simulator (e.g., `platform robot | platform simulator`). Up to three key-value pairs can be provided to identify the type of animate behavior to exhibit (e.g., `behavior body | behavior hands | behavior rotation`). One key-value pair will specify the range of actuator movement, specified as a percentage of half the full range of movement (e.g., `range 5`). One key-value pair will specify the filename of the file in which the physical Pepper robot sensor and actuator topic names are stored (e.g., `robotTopics pepperTopics.txt`). One key-value pair will specify the filename of the file in which the simulator sensor and actuator topic names are stored (e.g., `simulatorTopics simulatorTopics.txt`). The configuration file will be named `animateBehaviorConfiguration.txt`.

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through files, or ROS subscribers, services, or actions. Based on the module specification in the task description, it is planned that the interface of this module will use both the physical robot and the simulator to sink the control data published on the various actuator topics, after having been resent by the Gesture, Speech, and Navigation subsystem. For this reason, a stub will be developed to subscribe to the topics published by this module and resend the messages to either the physical robot or the simulator.

The module design section will specify selected message data structures used to represent and store the topic messages required to control the actuators.

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

The unit testing section will present the unit tests. At least two types of unit test will be delivered: (i) verification against module specification, and (ii) validation against requirements definition. A test report will document the results of these tests.

Finally, a user manual will be included in the deliverable, explaining how to invoke, provide input to, and configure the `animateBehavior` module.



## Description of Deliverables (continued)

### D5.3 Attention Subsystem

*Deliverable type: software and report*

This deliverable represents the outcome of Task 5.3. It comprises the documented software required to build and launch a module implemented as a single ROS node that provides the robot with the ability to pay attention to salient features in its environment. The ROS node will be named `overtAttention`.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in the task description, identifying gaps and misalignments with actual needs.

The module specification section will define the functional characteristics, i.e., direct the gaze of the robot at salient features associated with social interaction, e.g., people's bodies, faces, eyes, and voices, both when the robot is interacting with people and when it is just observing its environment. When observing the environment, the robot will also fixate on other interesting features or objects. In this mode of operation, the robot will change its focus of attention after some time and not return directly to the original focus of attention. Two saliency maps will be generated, one based on social feature and one based on general interesting features. The former will use the output of Task 4.2.2 Face & Eye Detection and Localization and Task 4.2.3 Sound Detection and Localization. Candidates for the latter include the Itti and Koch saliency model of visual attention (Itti et al., 1998; Itti & Koch, 2000, 2001), the model proposed by Rea et al. (2013), the information-theoretic saliency map (Bruce & Tsotsos, 2009), and open source deep neural network saliency models. The complete overt attention system will comprise (a) a winner-take-all process effected by a selective tuning model to identify a single focus of attention (Tsotsos et al., 1995; Tsotsos, 2006, 2011), (b) an Inhibition-of-Return (IOR) mechanism to attenuate the attention value of previous winning locations so that new regions become the focus of attention, and (c) a habituation process to reduce the salience of the current focus of attention with time thereby ensuring that attention is fixated on a given point for a limited period (Zaharescu et al., 2004). Furthermore, attention will also be directed towards conspicuous sounds. Aural attention will have a higher priority than visual attention.

The robot's gaze will be directed by publishing the appropriate control messages on the `headYaw` and `headPitch` actuator topics so that the gaze is centred on the focus of attention. This requires the calibration of the x and y offset of the focus of attention in the image to the change in `headYaw` and `headPitch` angles, respectively. In the case of aural attention to conspicuous sounds, it requires the calibration of the angle of arrival of the sound with the change in `headYaw` angle. Fixation on sounds will only control the `headYaw` angle, i.e., rotation in the horizontal plane about the head's z axis. These calibration constants will be provided as parameters to the module. If the angle of rotation of the `headYaw` is greater than some threshold defined as a parameter, then after rotating the head to fixate on the focus of attention, the base of the robot and the head will rotate in opposite directions so that the robot continues to gaze at the focus of attention as it realigns its head with its body. The threshold for this realignment will be provided as a parameter to the module.

## Description of Deliverables (continued)

One input will take the form of an RGB image from one of the robot's cameras (forward facing or RGB-D). Other inputs are the outputs of the modules in deliverables D4.2.2 Face & Eye Detection and Localization and D4.2.3 Sound Detection and Localization.

One output will take the form of an RGB image depicting the saliency function and the selected focus of attention. Other outputs are the control messages, published on the appropriate topics, to adjust the headYaw, headPitch, and, if required, the orientation of the robot. The image will be published on a topic named `saliencyImage`.

The names of the topics to be used for each actuator will be read from a data file comprising a sequence of key-value pairs. The key is the name of the actuator. The value is the topic name. There will be two data files, one for the physical robot and another for the simulator.

The operation of the attention module is determined by the contents of a configuration file that contains a list of key-value pairs. One key-value pair will specify the platform on which the tests are to be run, i.e., the physical Pepper robot or the Pepper simulator (e.g., `platform robot | platform simulator`). One key-value pair will specify the RGB camera to be use (e.g., `camera topCamera | camera depthCamera`). One key-value pair will specify the threshold on the angular difference between head and base that must be met before the head and base are realigned (e.g., `realignmentThreshold 5`). One key-value pair will specify the calibration constant that defines the conversion the offset in the x (horizontal) axis of an image from the image center to the change in headYaw angle (e.g., `xOffsetToHeadYaw 25`). One key-value pair will specify the calibration constant that defines the conversion the offset in the y (vertical) axis of an image from the image center to the change in headPitch angle (e.g., `yOffsetToHeadPitch 20`). One key-value pair will specify the filename of the file in which the physical Pepper robot sensor and actuator topic names are stored (e.g., `robotTopics pepperTopics.txt`). One key-value pair will specify the filename of the file in which the simulator sensor and actuator topic names are stored (e.g., `simulatorTopics simulatorTopics.txt`). The configuration file will be named `overtAttentionConfiguration.txt`.

The names of the topics to be used for each actuator will be read from a data file comprising a sequence of key-value pairs. The key is the name of the actuator. The value is the topic name. There will be two data files, one for the physical robot and another for the simulator. The input data file for the physical robot will be named `pepperTopics.txt`. The input data file for the simulator will be named `simulatorTopics.txt`.

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through files, or ROS subscribers, services, or actions. Based on the module specification in the task description, it is planned to develop a driver to generate test input data, invoking the faceDetection and soundDetection modules, and, in the event that the Pepper robot is not available for testing, acquiring the RGB image from an external camera. It is planned that the module will use both the physical robot and the simulator to sink the control data published on the various actuator topics.

## Description of Deliverables (continued)

The module design section will specify selected message data structures used to represent and store the topic messages required to control the actuators, and the image data structures, and saliency, focus of attention selection, habituation, and inhibition-of-return algorithms.

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

The unit testing section will present the unit tests. At least two types of unit test will be delivered: (i) verification against module specification, and (ii) validation against requirements definition. A test report will document the results of these tests.

Finally, a user manual will be included in the deliverable, explaining how to invoke, provide input to, and configure the overtAttention module.

### **D5.4.1 Culture Knowledge Ontology& Knowledge Base**

*Deliverable type: software and report*

This deliverable comprises a cultural knowledge ontology and a related knowledge base that, together, formalize the culturally sensitive knowledge that is documented in Deliverables D1.2 African Modes of Social Interaction and D1.3 Africa-centric Design Patterns. It provides the basis for generating culturally sensitive actions by the robot when interacting with visitors in the use case demonstrations.

### **D5.4.2 Scenario Script Language**

*Deliverable type: report*

This deliverable defines a language that can be used to formally specify the interactions in the use case scenarios as interaction scripts and enact them in a culturally sensitive manner using the cultural knowledge ontology and cultural knowledge base. It provides the specification for the implementation of an interpreter that can translate this scripted specification into robot actions, thereby enacting the use case scenarios defined in Task 2.1 and documented in Deliverable D2.1. The outcome of this task, which includes the specification of the language and the specification of the two use scenarios in that language, is described in Deliverable D5.4.2.

### **D5.4.3 Scenario Script Interpreter**

*Deliverable type: software and report*

This deliverable represents the outcome of Task 5.4.3. It comprises the documented software required to build and launch a module implemented as a single ROS node that interprets the scenario script language developed in Task 5.4.2 and implements the specification of the two use scenarios in that language, as documented in Deliverable D5.4.2. It does so by recruiting the robot and visitor behaviors documented in Deliverables D2.2 and D2.3, and the cultural knowledge encapsulated in Deliverable D5.4.1, and realized in the robot sensing modules developed in Work Package 4 and the robot behavior modules developed in Work Package 5. The outcome of this task is described in Deliverable D5.4.3.

## Description of Deliverables (continued)

### D5.5.1 Gesture Execution

*Deliverable type: software and report*

This deliverable represents the outcome of Task 5.5.1. It comprises the documented software required to build and launch a module implemented as a single ROS node that provides the robot with the ability to the Pepper robot to execute body and hand gestures. Hand gestures will include deictic, symbolic, and iconic non-verbal gestures. Body gestures will be restricted to bowing and nodding, i.e., lowering and raising gaze. The ROS node will be named `gestureExecution`.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in the task description, identifying gaps and misalignments with actual needs.

The module specification section will define the functional characteristics, as follows. The module will execute five forms of gesture: deictic, symbolic, and iconic non-verbal hand gestures and bowing and nodding body gestures. The specifications for these gestures will be in joint space, rather than Cartesian space. Some gestures, e.g., iconic and symbolic hand gestures will be specified by learning the required motions either by manual teleoperation, recording the joint angles, or by demonstration, using an RGB-D depth camera to determine the joint angles of human gestures in a skeletal model and mapping these to the robot joints. Other gestures, i.e., deictic hand gestures and body gestures, will be specified by gesture parameters, such as the pointing direction for deictic gestures and the degree of inclination for bowing and nodding, and the joint angles will be computed using the kinematic model of the robot head, torso, and arms. For deictic gestures, which require the robot to point at objects in its environment, the pose of the robot in the world frame of reference will also be used.

Iconic and symbolic gestures will be defined by descriptors that specify the final gesture joint configuration and the manner in which that configuration is achieved. Descriptors comprise four elements. Each element is a key-value pair, where the value can be an identifier, a number, a vector of numbers, or a vector of a vector of numbers. The first key-value pair will specify the gesture type (e.g., `type iconic` | `type symbolic`). The second key-value pair will identify the ID number (e.g., `ID 01`). The third element defines the number of waypoints in the trajectory, including the start gesture joint configuration and the final gesture joint configuration. The fourth element is a vector of joint angles vectors. The number of joint angle vectors is equal to the number of way points, including the start joint configuration and the final gesture configuration. Body gestures have three joints: knee pitch, hip pitch, hip roll. Iconic and symbolic gestures have five joints: shoulder pitch, shoulder roll, elbow yaw, elbow roll, and wrist yaw. Before beginning the gesture, the arm is moved from its current joint configuration to the start joint configuration, i.e., the joint angles specified in the first vector in the vector of vector of joint angles. The number of elements in the vector of joint angles is determined by the gesture type. Descriptors for each gesture will be stored in an external descriptor file.

## Description of Deliverables (continued)

If an iconic or symbolic gesture involves two arms, they will be treated as a composite of two individual gestures, one for each arm.

Two approaches will be investigated to determine the joint angles for iconic and symbolic hand gestures. The first will involve the manual adjustment and recording of each joint by an operator. This will be done for each waypoint in the gesture. The second will involve learning the joint angles by demonstration, using an RGB-D camera and body tracking software with a skeleton model. In both cases, these angles will be in the gesture descriptor file and read from the file at run time.

The joint angles for bow and nod body gestures, as well as hand deictic gestures, will be computed at run time using the kinematic model of the robot and the bow angle, nod angle, or the location in the environment to which the robot should point. The bow angle, nod angle, and pointing location will be provided as an input to the module, along with the time in milliseconds that should elapse between the start of the gesture and the end of the gesture. The pointing direction with respect to the robot body, specified by the shoulder pitch and shoulder roll angles, will be computed from the pointing location in the world frame of reference (and supplied as an input to the module) and the pose of the robot in the world frame of reference (provided by the module in Deliverable 4.4). No waypoints are required for deictic gestures; the joints will be actuated to achieve the target joint angles, interpolating linearly or adjusting the joint angles, joint angular velocities, and joint accelerations to mimic biological motion by using a kinematic model of biological motion (e.g., a power law or a minimum jerk law). It is assumed that the knee pitch angle is fixed during a bow body gesture and that the bow angle corresponds to the change in the hip pitch angle with respect to the default hip pitch angle. Similarly, it is assumed that the nod angle is the change in the head pitch angle with respect to the default head pitch angle. Finally, it is assumed that the arm and fingers are straight in a deictic gesture, with fixed values of elbow yaw, elbow roll, wrist yaw, and hand angles, so that the palm of the hand is directed upwards.

The input to the module will be a record comprising the gesture type (e.g., iconic | symbolic | deictic | bow | nod), the gesture ID for symbolic or iconic gestures (e.g., 01), the duration of the gesture in milliseconds, and either a bow angle in degrees (for a bow body gesture), or a nod angle in degrees (for a nod body gesture), or the three dimensional coordinates of a pointing location (for a deictic gesture). For deictic gestures, the module will also input the current robot pose from the robotLocalization module.

The output will be a sequence of joint angles, joint angular velocities, and, optionally, joint angular accelerations. Data will be published on the appropriate topics, as required; ROS actions will also be used where necessary.

The names of the topics to be used for each actuator will be read from a data file comprising a sequence of key-value pairs. The key is the name of the actuator. The value is the topic name. There will be two data files, one for the physical robot and another for the simulator.

## Description of Deliverables (continued)

The operation of the `gestureExecution` module is determined by the contents of a configuration file that contains a list of key-value pairs. One key-value pair will specify the platform on which the tests are to be run, i.e., the physical Pepper robot or the Pepper simulator (e.g., `platform robot | platform simulator`). One key-value pair will specify the interpolation type. This indicates how the joint angles that define the trajectory in joint space between the current joint angles and the gesture joint angles are to be computed for body gesture and hand deictic gestures, and between way points for iconic and symbolic gestures. At least two options will be considered: (a) independent linear interpolation of each joint angle, and (b) biological motion, selecting the sequence of joint angular velocities and joint accelerations to form a trajectory in time and joint space that mimics biological motion (e.g., `interpolation linear | interpolation biological`). One key-value pair will specify the filename of the file in which the gesture descriptors are stored (e.g., `gestureDescriptors gestureDescriptors.txt`). One key-value pair will specify the filename of the file in which the physical Pepper robot sensor and actuator topic names are stored (e.g., `robotTopics pepperTopics.txt`). One key-value pair will specify the filename of the file in which the simulator sensor and actuator topic names are stored (e.g., `simulatorTopics simulatorTopics.txt`). The configuration file will be named `gestureExecutionConfiguration.txt`.

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through files, or ROS subscribers, services, or actions. Based on the module specification in the task description, it is planned to develop a driver to generate test input data and publish it on the topic to which the `gestureExecution` module subscribes for command input. It is planned that the module will use both the physical robot and the simulator to sink the control data published on the various actuator topics.

The module design section will specify selected message data structures used to represent and store the topic messages required for command input and to control the actuators, and the algorithms required to change frames of reference and compute the required joint angles.

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

The unit testing section will present the unit tests. At least two types of unit test will be delivered: (i) verification against module specification, and (ii) validation against requirements definition. A test report will document the results of these tests.

Finally, a user manual will be included in the deliverable, explaining how to invoke, provide input to, and configure the `gestureExecution` module.

## Description of Deliverables (continued)

### D5.5.2 Text to Speech Conversion

*Deliverable type: software and report*

This deliverable represents the outcome of Task 5.5.2. It comprises the documented software required to build and launch a module implemented as a single ROS node that converts the text to speech, specifically the text of the robot's interactions specified in Deliverable D2.2 Robot Behavior Specification and recruited in Deliverable D5.4.2 Scenario Script Language. While the primary language of communication will be English, in anticipation of more natural interaction in the future, we will also address text to speech for Kinyarwanda speakers, so that Pepper will be able to use its voice to provide spoken greetings and responses in Kinyarwanda. The possibility of controlling loudness, pitch, and timbre of the speech will be investigated. The ROS node will be named `TTSTConversion`.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in this work plan, identifying gaps and misalignments with actual needs.

The module specification section will define the functional specification, detailing the input to output data transformation, expected input data, expected output data, module configuration parameters, and a draft user manual. Functionally, this module will use a speech synthesis engine to convert English or Kinyarwanda text to an audio file that can then be played on the robots loudspeakers. The operation of the module will be determined by parameters provided in a configuration file. The operation of the `gestureExecution` module is determined by the contents of a configuration file. This configuration file will contain two key-value pairs. One key-value pair the language to be used (e.g., `language English | lanaguage Kinyarwanda`). The configuration file will be named `TTSTConversionConfiguration.txt`.

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through ROS topics, services, or actions. In addition, it will include the specification of a driver to source test input data, and a specification of stub to sink test output data. Based on the module specification, it is planned to develop a driver to generate test data based on parameters defined in the driver input file, using text defined in the Deliverable D2.2 Robot Behavior Specification. It is planned to develop a stub to sink the output data and play the audio file on a PC.

The module design section will specify selected algorithms and data structures, and develop a unit test plan. It is planned to investigate the feasibility of using the NAOqi audio utility `ALTextToSpeech` through a ROS interface and adapting an open source speech synthesis engine for Kinyarwanda, possibly leveraging work by Rutunda et al. (2023).

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

### **Description of Deliverables (continued)**

The unit testing section will present the unit tests. At least two types of unit test will be delivered: (i) verification against module specification, and (ii) validation against requirements definition. Where feasible, an evaluation unit test against benchmark data or standard metrics will be delivered. A test report will document the results of these tests.

In addition, a user manual will be included in the deliverable, explaining how to invoke, provide input to, and configure the module.



## Description of Deliverables (continued)

### D5.5.3 Environment Map Generation

*Deliverable type: software and report*

This deliverable represents the outcome of Task 5.5.3. It comprises the documented software required to build and launch a module implemented as a single ROS node that generates metric workspace and configuration space maps of the environments that will be used in the two use case scenarios documented in Deliverable D2.1, augmented by the locations and identities of objects of interest, as specified in the use case scenarios. Thus the map will comprise both non-symbolic metric data and symbolic semantic data. These maps will be used by the Pepper robot when navigating and when making deictic gestures. The ROS node will be named `mapGeneration`.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in this work plan, identifying gaps and misalignments with actual needs.

The module specification section will define the functional specification, detailing the input to output data transformation, expected input data, expected output data, module configuration parameters, and a draft user manual. Functionally, this module will generate a workspace metric map, augmented by a list of the locations and identities of objects and regions of interest to which the robot can refer to and point to when interacting with humans. Such objects include walls, floor furniture, wall furniture, plants, steps (up and down), doors and doorways, signs, and elevators. This object-location data is to be generated interactively by displaying the workspace map in a window and allowing a user to use a cursor to identify a location and label it with a single-word identifier. These identifiers should correspond to the labels that are used in the use case scenario description in Deliverable D6.1 written using the scenario script language in Deliverable D5.4.2.

The input to the module will be a record comprising the filenames of the files to which the workspace and configuration space maps are to be written, and the data file in which the list of labelled objects of interest and their locations on the maps is to be stored.

The output will be a non-symbolic metric data map of the environment workspace, and a list of labelled objects of interest and their locations on the maps. The map should be in a format that can be rendered as an image. Data will be published on the appropriate topics.

The operation of the module will be determined by parameters provided in a configuration file that contains a list of key-value pairs. One key-value pair will specify the platform on which the tests are to be run, i.e., the physical Pepper robot or the Pepper simulator (e.g., `platform robot` | `platform simulator`). One key-value pair will specify the map generation mode, i.e., using CAD data or SLAM (e.g., `mode CAD` | `mode SLAM`). The configuration file will be named `mapGenerationConfiguration.txt`.

## Description of Deliverables (continued)

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through ROS topics, services, or actions. In addition, it will include the specification of a driver to source test input data, and a specification of stub to sink test output data. Based on the module specification, it is planned that the interface of this module will develop a driver to generate test data for CAD mode based on parameters defined in the driver input file, i.e., the geometric specification the geometry of the environment for each use case. It is planned to develop a stub to sink the output data and display the metric map image of the workspace using OpenCV, with the workspace image annotated with the object labels at the appropriate locations.

The module design section will specify selected algorithms and data structures, and develop a unit test plan. It is planned to adopt two strategies: (i) map generation from a priori data (i.e., environment CAD data) and (ii) map generation using Simultaneous Localization and Mapping (SLAM).

The software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The anticipated outputs of each of these phases are detailed in the associated deliverable description. The outcome of these phases are described in Deliverable D5.5.3.

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

The unit testing section will present the unit tests. At least two types of unit test will be delivered: (i) verification against module specification, and (ii) validation against requirements definition. Where feasible, an evaluation unit test against benchmark data or standard metrics will be delivered. A test report will document the results of these tests.

In addition, a user manual will be included in the deliverable, explaining how to invoke, provide input to, and configure the module.

## Description of Deliverables (continued)

### D5.5.4 Robot Navigation

*Deliverable type: software and report*

This deliverable represents the outcome of Task 5.5.4. It comprises the documented software required to build and launch a module implemented as a single ROS node that controls the locomotion of the Pepper robot so that it navigates its environment, in which there are fixed inanimate obstacles and moveable obstacles in the form of humans, from its current position along the shortest path to a destination position and orientation identified in the use case scenario script. Navigation will be effected by identifying waypoints along the navigation path and the robot will move from waypoint to waypoint. The ROS node will be named `robotNavigation`.

In addition to functional code, the deliverable will include a report with sections detailing the outputs of each phase of the software development process.

The requirements definition section will specify the functional needs of users of the module. This will involve a review and update of the requirements as set out in this work plan, identifying gaps and misalignments with actual needs.

The module specification section will define the functional specification, detailing the input to output data transformation, expected input data, expected output data, module configuration parameters, and a draft user manual. Functionally, this module will optionally augment a metric workspace map of the robot's environment with obstacles corresponding to the location of any humans that have been detected in the robot's field of view. The size of the human obstacle will be determined using culturally sensitive proxemics. This augmented workspace map will then be used to generate a configuration space map that constrains the robot's path from its current location to its target location using either Dijkstra's algorithm and the A\* algorithm. Waypoints will be identified using one of two candidate techniques: equidistant waypoints and high path curvature waypoints. Locomotion from waypoint to waypoint will be effected using one of two locomotion algorithms: Multiple Input Multiple Output (MIMO) and divide and conquer (DnQ).

The input to the module will be a record identifying the destination pose for the robot, specified by the x and y coordinates of the location and the direction the robot should face (i.e., the direction of the x axis in the robot base frame, all specified in the workspace frame of reference). The module will also acquire the robot's current pose using the module in Deliverable D4.2.1 Person Detection and Localization, the cultural knowledge regarding proxemics in a file produced in Deliverable D1.2 African Modes of Social Interaction, and the workspace map in a file produced in Deliverable D5.5.3.

The output will be a sequence of forward velocity and angular velocity values published on the `cmd_vel` topic. The configuration space map will also be published in a format that can be rendered as an image. The planned path will be rendered graphically on this map.

The names of the topics to be used for each actuator will be read from a data file comprising a sequence of key-value pairs. The key is the name of the actuator. The value is the topic name. There will be two data files, one for the physical robot and another for the simulator.

## Description of Deliverables (continued)

The operation of the module will be determined by parameters provided in a configuration file containing a list of key-value pairs. One key-value pair will specify the platform on which the tests are to be run, i.e., the physical Pepper robot or the Pepper simulator (e.g., `platform robot | platform simulator`). One key-value pair will specify the filename of the file in which the workspace map is stored (e.g., `map scenarioOneMap`). One key-value pair will specify the filename of the file in which the culturally sensitive social knowledge is stored (e.g., `culturalKnowledge culturalKnowledgeData.txt`). One key-value pair will specify the path planning algorithm to be used (e.g., `pathPlanning Dijkstra | pathPlanning A*`). One key-value pair will specify the number of waypoints to be used (e.g., `waypointNumber 5`). One key-value pair will specify the waypoint selection criterion to be used (e.g., `waypointSelection equidistant | waypointSelection curvature`). One key-value pair indicates whether or not to take into consideration social constraints while navigating (e.g., `socialDistance TRUE | socialDistance FALSE`). One key-value pair will specify the filename of the file in which the physical Pepper robot sensor and actuator topic names are stored (e.g., `robotTopics pepperTopics.txt`). One key-value pair will specify the filename of the file in which the simulator sensor and actuator topic names are stored (e.g., `simulatorTopics simulatorTopics.txt`). The configuration file will be named `robotNavigationConfiguration.txt`.

The interface design section will include a specification of the data that are input to the module, the data that are output from the module, and the data that are used to control the operation of the module, including the manner in which this data is made available or accessed, either through ROS topics, services, or actions. In addition, it will include the specification of a driver to source test input data, and a specification of stub to sink test output data. Based on the module specification, it is planned to develop a driver to generate test data, i.e., target robot poses for each use case scenario workspace map. It is planned to develop a stub to sink the output data and display the metric map images of the workspace and configuration space using OpenCV.

The module design section will specify selected algorithms and data structures, and develop a unit test plan. It is planned to adopt two path planning algorithms (Dijkstra's algorithm and the A\* algorithm), two waypoint selection algorithms (equidistant and high curvature waypoints). Image dilation will be used to convert the workspace map to a configuration space map, using a structuring element that models the size and shape of the robot's base.

The software development process will involve requirements definition, module specification, interface design, module design, coding, and unit testing. The anticipated outputs of each of these phases are detailed in the associated deliverable description. The outcome of these phases are described in Deliverable D5.5.3.

The coding section will contain the functional program code with internal documentation, any required build files, driver program code, and stub program code. Code will be written and documented in adherence to the standards to be developed in Deliverable D3.2 Software Engineering Standards Manual.

### **Description of Deliverables (continued)**

The unit testing section will present the unit tests. At least two types of unit test will be delivered: (i) verification against module specification, and (ii) validation against requirements definition. Where feasible, an evaluation unit test against benchmark data or standard metrics will be delivered. A test report will document the results of these tests.

In addition, a user manual will be included in the deliverable, explaining how to invoke, provide input to, and configure the module.

Work Package Number	6
Work Package Title	Use Case Demonstration and Evaluation

## Objectives

1. Carry out initial demonstrations of the system architecture in the two use cases.
2. Evaluate the success of the demonstrations and identify any adjustments the output from work packages WP1 - WP5.
3. Carry out final demonstrations.
4. Re-evaluate the success of the demonstrations.

## Description of Work

### Task 6.1: Use Case Implementation (M19–M21)

*Lead Partner:*

*Participating Partner:*

The objective of this task is to implement both use cases using the outcomes of WP1 - WP5, i.e., the cultural knowledge, the scenario specification, and the integrated robot's sensory and interaction capabilities. This objective will be achieved by running the unit test and system tests in Deliverable D3.3. The outcome of this task is described in Deliverable D6.1.

### Task 6.2: Use Case Evaluation (M22–M24)

*Lead Partner:*

*Participating Partner:*

The objective of this task is to evaluate the implementations using the Robot Social Attribute Scale (RoSAS) and produce a set of required adjustments for the interaction primitives and design patterns. The task uses the outcome of Task 6.1 as documented in Deliverable D6.1. The outcome of this task is described in Deliverable D6.2.

### Task 6.3: Use Case Re-Evaluation (M34–M36)

*Lead Partner:*

*Participating Partner:*

The objective of this task is to re-evaluate the implementation after completion of the adjustments in work packages WP1 – WP5 arising from the evaluation in Task 6.2. The outcome of this task is described in Deliverable D6.3.

## List of Deliverables

Number	Deliverable Title	Lead Partner	Delivery Month
D6.1	Use Case Implementation		M21
D6.2	Use Case Evaluation		M24
D6.3	Use Case Re-Evaluation		M36

## Description of Deliverables

### **D6.1 Use Case Implementation**

*Deliverable type: demonstration and report*

This deliverable represents the outcome of Task 6.1. It is a demonstration of the complete working system for the two use cases defined in Work Package WP2.

### **D6.2 Use Case Evaluation**

*Deliverable type: report*

This deliverable represents the outcome of Task 6.2. It will be evaluated and document the success of the initial use case implementation using the Robot Social Attribute Scale (RoSAS).

### **D6.3 Use Case Re-Evaluation**

*Deliverable type: report*

This deliverable represents the outcome of Task 6.3. It will document the success of the final use case implementation using the Robot Social Attribute Scale (RoSAS).

Work Package Number	7
Work Package Title	Dissemination and Impact

## Objectives

1. Create a project website.
2. Disseminate the ongoing status of the project in several forums, including the project website.
3. Publish research results in conferences and journals.
4. Make the project software and data freely available online.
5. Organize a summer school.

## Description of Work

### **Task 7.1: Online Presence (M1–M48)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to communicating project aims and results to the general public and stakeholders. This objective will be achieved by creating a project website to describe the motivation for and goals of the project, to periodically post updates on progress, and highlight results, including publications and forthcoming events. The outcome of this task is described in Deliverable D7.1.

### **Task 7.2: Dissemination Activities (M1–M36)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is effect scientific dissemination through leading international conferences and journals, as well as through forums such as AI Saturdays, Knowledge for All (K4All), and AI4D. A record of all communication actions will be kept and incorporated in a yearly dissemination and communication report. The outcome of this task is described in Deliverable D7.2.

### **Task 7.3: Open-Source Software, Data, and Designs (M18–M36)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to make code, data, protocols publicly available on GitHub and maintain the repositories. The outcome of this task is described in Deliverable D7.3.

### **Task 7.4: Summer School (M34–M36)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to organise a summer school on culturally-sensitive human-robot interaction in 2026. The outcome of this task is described in Deliverable D7.4



## List of Deliverables

Number	Deliverable Title	Lead Partner	Delivery Month
D7.1	Online Presence		M6
D7.2	Dissemination Activities		M12, M24, M36
D7.3	Open-Source Software, Data, and Designs		M18, M36
D7.4	Summer School		M34

## Description of Deliverables

### D7.1 Online Presence

*Deliverable type: website*

This deliverable represents the outcome of Task 7.1. It is an operational website detailing the goals, status, and results of the project. It will be delivered at month 6 and will be maintained throughout the duration of the project.

### D7.2 Dissemination Activities

*Deliverable type: report*

This deliverable represents the outcome of Task 7.2. It documents the reports, papers, articles, presentations, and demonstrations that have been carried out. Three versions of the deliverable will be produced, one at the end of each year.

### D7.3 Open-Source Software, Data, and Designs

*Deliverable type: online repository*

This deliverable represents the outcome of Task 7.3. It is a GitHub software repository of the software and data (i.e., the cultural knowledge) developed in the project. The initial repository will be created by month 18. The final repository at month 36.

### D7.4 Summer School

*Deliverable type: event and report*

This deliverable represents the outcome of Task 7.4. It will be organized at the end of the project, to enable the wider community to use the results of the project.

Work Package Number	8
Work Package Title	Project Management

## Objectives

1. Carry out coordination, finance, and management activities.
2. Prepare and sign a consortium agreement.
3. Prepare and execute a gender action plan.

## Description of Work

### **Task 8.1: Project Coordination (M1–M36)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is coordinate the technical work in the project. Progress in each work package and each task will be monitored weekly to identify any potential issues and to take the appropriate timely corrective actions. This task will involve the organization of in-person project meetings every three months and writing six-monthly project progress reports, including a final report setting out the project activities, significant accomplishments, and reference to published papers. For day-to-day communication and coordination, we will set up a Discord platform dedicated to the projects, with individual channels for each work package and each task. The outcome of this task is described in Deliverable D8.1.

### **Task 8.2: Administration (M1–M36)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is to plan and monitor financial expenditure, and submit periodic financial reports. The outcome of this task is described in Deliverable D8.2.

### **Task 8.3: Risk Management (M1–M36)**

*Lead Partner:*

*Participating Partner:*

Initial risks and appropriate mitigation strategies have already been identified in Table 4. The objective of this task is to focus on monitoring these risks as the project progresses, and take appropriate corrective actions, where necessary. It also monitors the possible emergence of new risks and updates the risk plan accordingly. Any updates will be reported in periodic reports. The outcome of this task is described in Deliverable D8.3.

### **Task 8.4: Consortium Agreement (M1–M4)**

*Lead Partner:*

*Participating Partner:*

The objective of this task is draft and agree a consortium agreement under which the rights and obligations of the partners are set out, with particular attention being paid to intellectual property rights, and the agreement of an appropriate open source licence to be adopted for all project deliverables. The outcome of this task is described in Deliverable D8.4.

## Description of Work (continued)

### Task 8.5: Gender Action Plan (M1–M4)

*Lead Partner:*

*Participating Partner:*

The objective of this task is to draft a gender action plan with the specific intent of ensuring there is no gender bias in any activity directed at stakeholders, i.e., in the ethnographic studies and in the execution and evaluation of the two use cases. The outcome of this task is described in Deliverable D8.5.

## List of Deliverables

Number	Deliverable Title	Lead Partner	Delivery Month
D8.1	Progress Report		M6, M12, ..., M36
D8.2	Expenditure Report		M6, M12, ..., M36
D8.3	Risk Assessment		M12, M24, M36
D8.4	Consortium Agreement		M4
D8.5	Gender Action Plan		M4

## Description of Deliverables

### D8.1 Progress Report

*Deliverable type: report*

This deliverable represents the outcome of Task 1task number1.

This deliverable documents progress in each work package and in each task. It is produced every six months. A final report will be produce in month 36 at the end of the project. This report will set out the project activities, significant accomplishments, and reference to published papers.

### D8.2 Expenditure Report

*Deliverable type: report*

This deliverable represents the outcome of Task 8.2. It summarizes the financial standing of the project under each budget heading. It is produced every six months.

### D8.3 Risk Assessment

*Deliverable type: report*

This deliverable represents the outcome of Task 8.3. It documents any risk mitigation actions that have been taken. It is produced at the end of each year.

### D8.4 Consortium Agreement

*Deliverable type: report*

This deliverable represents the outcome of Task 8.4. It sets out the rights and obligations of the partners regarding intellectual property rights. It also identifies the open source licence that is adopted for all project deliverables.

### D8.5 Gender Action Plan

*Deliverable type: report*

This deliverable represents the outcome of Task 8.5. It documents the actions that are to be taken to ensure that there is no gender bias in any activity directed at stakeholders, i.e., in the ethnographic studies and in the execution and evaluation of the two use cases.

Table 3: List and Schedule of Milestones

Number	Milestone Title	Related WP No.	Month	Means of Verification
M1	Completion of study to acquire African cultural knowledge	WP1	6	D1.1
M2	System architecture complete	WP3	9	D3.1
M3	Software implementation phase 1 complete	WP3, WP4, WP5	18	D3.3
M4	Use cases implementation and evaluation phase 1 complete	WP6	24	D6.2
M5	Software implementation phase 2 complete	WP4, WP5	33	D3.3
M6	Use cases implementation and evaluation phase 2 complete	WP6	36	D6.3

Table 4: Critical risks for implementation

Description of Risk	WP Involved	Risk Mitigation Strategy
African cultural knowledge are not effective in use cases	WP3, WP6	T6.2 produces a set of required adjustments which are then implemented in T1.4.
Implementation of the system architecture for use cases is insufficient	WP3	T6.2 produces a set of required adjustments which are then implemented in T3.5
Robot sensing and analysis does not perform adequately	WP4	T6.2 produces a set of required adjustments which are then implemented in T4.4
Robot behaviors do not perform adequately	WP5	T6.2 produces a set of required adjustments which are then implemented in T5.6.
T6.4 Use case evaluation does not achieve sufficiently high user ratings in the evaluation	WP1–WP6	T6.2 identifies adjustments; these are implemented in T1.4, T2.4, T3.5, T4.4, and T5.6.

Table 5: Summary of effort

Partner	WP1	WP2	WP3	WP4	WP5	WP6	WP7	WP8	Total
Carnegie Mellon University Africa	3.02	1.89	1.89	7.05	4.02	3.35	1.52	1.25	24.00
University of the Witwatersrand	2.62	1.68	1.68	6.45	3.71	2.28	1.23	0.06	20.23
Total	5.64	3.57	3.57	13.50	7.73	6.15	2.75	1.31	44.23

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# Document History

## **Version 1.0**

First draft.  
8 June 2023.

## **Version 1.1**

Work packages WP4 and WP5 partially populated with task and deliverable descriptions.  
Typographical errors fixed throughout the document.  
9 June 2023.

## **Version 1.2**

Implemented several changes to address minor issues that arose as a consequence of the modifications introduced when producing Version 1.1.  
13 June 2023.

## **Version 1.3**

Reviewed WP4 and WP5, made changes and populated some tasks and deliverable descriptions.  
27 June 2023.

## **Version 1.4**

Updated appearance of cover page to be more consistent with the style of the deliverables.  
30 June 2023.

## **Version 1.5**

Set start date to July 1, 2023 to align with first six-monthly progress report in December 31, 2023, and final report in June 30, 2026, as specified in the grant agreement.  
Added lead partner and participating partner to each task.  
Revised and expanded task descriptions and deliverable descriptions in Work Packages 1 - 8 to adhere to a common format and level of detail.  
17 July 2023.