Project Proposal

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Abstract

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Lim et al. demonstrated a framework for dynamically mapping the emotion in a speech sample to robot gesturing [**?**]. Four parameters are identified that can be measured in the speech sample and applied to the robot's gesture; these are speed, intensity, regularity and extent. For example, speed is measured by the speech rate of the voice sample and applied to the velocity of the gesture. The use of these four parameters means that the emotional communication is pose-independent [contrasting with other research looking at specific gestures like arms up for suprise?]. Additionally, this is relatively simple(?) [compared to emotion generation models] because the robot requires no internal emotional state model. The framework was used to parameterise an example gesture on the NAO [more details on robot?] using actor speech samples and experiments were set up in order to test whether the resulting gesture successfully conveyed the emotional content of the original speech.

4 Risk Register

5 Timeline