COMPANION goals (Kirby thesis pp. 4-5)

• Minimizing the distance traveled to a goal, to conserve energy;

• Avoiding obstacles;

• Keeping a safety buffer around obstacles;

• Avoiding people, including keeping out of their personal space;

• Protecting the robot’s own “personal” space;

• Tending to the right when passing people;

• Keeping a default velocity, so as not to expend extra energy;

• Facing the direction of travel, but allowing for sidestepping obstacles as people do; and

• Maintaining forward inertia, rather than zig-zagging repeatedly, which is both inefficient and socially awkward.

US : we use first 4 (*maybe* we can use motion instructions that consider the last one? But not yet)