

Modules

- Module 1 –Cleaning Module
- Module 2 – Mobile module
- Module 3 – Entertainment Module
- Module 4 – Security Module
- Module 5 – Self-Charging
- Module 6 – Service Module
- Module 7–Emergency Assistance Module
- Module 8 – Elderly Help Module
- Module 9 – Reminder Module
- Module 10- Health-care Module
- Module 11 – Plant care Module
- Module 12- Shopping Module
- Module 13-Education Module
- Module 14-Interaction Module
- Module 15-Help-call Module
- Module 16-Remote Control Module

Robot's Tasks

- Helping for housework
- Maintaining security and reminder
- Communicating with people,entertain them and checking their health
- Communicating with people and serving as an assistant
- Serving as a receptionist
- Showing the way to the disabled
- Childminding
- Serving as a teacher for children
- Help People to do everyday tasks
- Communicate with people and help them in daily life

Example Social Robot Family

- Robot 1 (Maggie)
- Robot 2 (Robotman)
- Robot 3 (NAO)
- Robot 4 (Robovie)
- Robot 5 (Valerie)
- Robot 6
- Robot 7 (Jibo)
- Robot 8 (Pepper)
- Robot 9 (Reem-8)
- Robot 10 (PaPero)

Programming Assembly Robots In Terms Of Task Achieving Behavioural Modules First Experimental Results Dai Research Paper

Joe Jones, Daniel Roth



Programming Assembly Robots In Terms Of Task Achieving Behavioural Modules First Experimental Results Dai Research Paper:

Programming Assembly Robots in Terms of Task Achieving Behavioural Modules: First Experimental Results C. A. Malcolm, University of Edinburgh. Department of Artificial Intelligence, Tim Smithers, 1988 Journal of Design and Manufacturing, 1991 *Current Research in Britain*, 1990 Artificial Intelligence in Engineering Design R. A. Adey, Robert A. Adey, 1993 **British Reports, Translations and Theses** British Library. Document Supply Centre, British Library. Lending Division, 1989 Issue for Mar 1981 contains index for Jan Mar 1981 in microfiche form **Programming Robotic Assembly in Terms of Task Achieving Behavioural Modules** Tim Smithers, University of Edinburgh. Department of Artificial Intelligence, C. Malcolm, 1988 In this paper we propose a new approach to the programming of sensor based assembly robot systems for assembly tasks which aims to reduce or remove some of the current limitations We call this new approach programming in terms of task achieving behavioural modules *Behaviour-based Robotic Assembly Systems* Myra S. Wilson, 1993 Abstract This paper examines a method of improving the reliability of a Behaviour based robotic assembly system Robotic assembly systems in general suffer from the problem of variation and uncertainty build up which causes failure to complete the assembly correctly The Behaviour based approach to robotic assembly looks at decomposing the task into modular units called Behavioural Modules which reliably perform the assembly task Even so these Behavioural Modules can still fail due to the workcell conditions being outwith their competence This paper examines a method of using appropriate localised information to provide alternatives in the event of such a failure This introduces the concept of Exit States which inform the system of which internal control path was taken through a Behavioural Module the Ideal Execution Path the best control route through the hierarchy of Behavioural Modules and Alternative Execution Paths an alternative control route containing Behavioural Modules which can be used in the event of failure **The Use of Behavioural Modules to Simplify the Programming of Assembly Robots** Giovanni Cosimo Pettinaro, University of Edinburgh. Department of Artificial Intelligence, 1993 **Robot Behaviour** Ulrich Nehmzow, 2008-12-18 Robots have evolved impressively since the 3 D manipulator built by C W K ward 1957 the two little electromechanical turtles Elmer and Elsie Walter 1950 Walter 1951 and the rst mobile robots controlled by computers Shakey Nilsson 1984 CART Moravec 1979 Moravec 1983 and Iqbal et al 1979 Since then we have seen industrial robot manipulators working in car factories automatic guided vehicles moving heavy loads along predefined routes human remotely operated robots neutralising bombs and even semi autonomous robots like Sojourner going to Mars and moving from one position to another commanded from Earth Robots will go further and further in our society However there is still a kind of robot that has not completely taken off so far autonomous robots Autonomy depends upon working without human supervision for a considerable amount of time taking independent decisions adapting to new challenges in dynamic environments interacting with other systems and

humans and so on Research on autonomy is highly motivated by the expectations of having robots that can work with us and for us in everyday environments assisting us at home or work acting as servants and companions to help us in the execution of different tasks so that we can have more spare time and a better quality of life

Applying Genetic Programming to Evolve Behavior Primitives and Arbitrators for Mobile Robots Wei-Po Lee, John Hallam, University of Edinburgh. Department of Artificial Intelligence, Henrik H. Lund, 1996 Abstract Behavior based approach has been successfully applied to design the control system of a robot This paper presents our approach based on evolutionary algorithms to program behavior based robots automatically Instead of handcoding all the behavior controllers or evolving an entire control system for an overall task we suggest our approach at the intermediate level it includes evolving behavior primitives and behavior arbitrators for a mobile robot to achieve the specified tasks To examine the developed approach we evolve a control system for a moderate complicated box pushing task as an example We first evolved the controllers in simulation and then transferred them to the Khepera miniature robot Experimental results show the promise of our approach and the evolved controllers are transferred to the real robot without loss of performance

A Behavioural Approach to Robot Task Planning and Off-line Programming T. Smithers, C. A. Malcolm, 1987

Robot Shaping Marco Dorigo, Marco Colombetti, 1998 foreword by Lashon Booker To program an autonomous robot to act reliably in a dynamic environment is a complex task The dynamics of the environment are unpredictable and the robots sensors provide noisy input A learning autonomous robot one that can acquire knowledge through interaction with its environment and then adapt its behavior greatly simplifies the designer's work A learning robot need not be given all of the details of its environment and its sensors and actuators need not be finely tuned Robot Shaping is about designing and building learning autonomous robots The term shaping comes from experimental psychology where it describes the incremental training of animals The authors propose a new engineering discipline behavior engineering to provide the methodologies and tools for creating autonomous robots Their techniques are based on classifier systems a reinforcement learning architecture originated by John Holland to which they have added several new ideas such as mutespec classifier system energy and dynamic population size In the book they present Behavior Analysis and Training BAT as an example of a behavior engineering methodology

Programming Autonomous Assembly Agents Lykourgos Petropoulakis, Chris Malcolm, 1990 It also reports on our experimental domain which is a complex form of the blocks world This naturally generalises to assembling walls from predominantly rectangular components and is designed to cope with variations in part size and location as a fundamental property of the domain

Achieving Reliability Using Behavioural Modules in a Robotic Assembly System Myra Scott Wilson, 1992

A Work-piece Based Approach for Programming Cooperating Industrial Robots Sherif Zaidan, 2013

Sensorimotor Primitives for Programming Robotic Assembly Skills James Daniel Morrow, 1997 Abstract This thesis addresses the problem of sensor based skill composition for robotic assembly tasks Skills are robust reactive strategies for executing recurring tasks in our domain In everyday life people rely extensively

on skills such as walking climbing stairs and driving cars proficiency in these skills enables people to develop and robustly execute high level plans Unlike people robots are unskilled unable to perform any task without extensive and detailed instructions from a higher level agent Building sensor based reactive skills is an important step toward realizing robots as flexible rapidly deployable machines Efficiently building skills requires simultaneously reducing robot programming complexity and increasing sensor integration which are competing and contradictory goals This thesis attacks the problem through development of sensorimotor primitives to generalize sensor integration graphical programming environments to facilitate skill composition and design integration for exploiting the primitive capabilities during task design Force and vision based sensorimotor primitives are built to provide sensor integration for task domains not task instances A task level graphical programming environment provides an intuitive interface for the designer programmer to compose the skill through a simple form of virtual demonstration Finally design agent representations of the primitives inside the CAD environment interact with the task model and the programmer to assist in composing the skill program Experimental results for six different assembly tasks demonstrate sensor based skill execution and illustrate primitive reusability

Achieving Reliability Using Behavioural Modules in a Robotic Assembly System Myra Scott Wilson,1992

Robot Programming Joe Jones,Daniel Roth,2004-01-02 Publisher's Note Products purchased from Third Party sellers are not guaranteed by the publisher for quality authenticity or access to any online entitlements included with the product MASTER ROBOT PROGRAMMING WITH YOUR OWN FREE VIRTUAL BOT This ingenious book Web site partnership teaches the skills you need to program a robot and gives you a virtual robot waiting online to perform your commands and test your programming expertise You don't need to know either robotics or programming to get started Using an intuitive method Robot Programming deconstructs robot control into simple and distinct behaviors that are easy to program and debug for inexpensive microcontrollers with little memory Once you've mastered programming your online bot you can easily adapt your programs for use in physical robots Though Robot Programming smoothes the path to acquiring skills in this arcane art it does not reduce it to simplistics With this resource you can open the door to all the complexity sophistication versatility and robustness that it is possible for robot behavior to exhibit WHAT DO YOU WANT YOUR ROBOT TO DO Robot Programming's hands on approach to behavior based robotics Teaches you intuitively with a system that integrates explanation code examples and exercises using an online robot simulator Demonstrates programming for mobile robots Gives you the tools to combine sensors with robot skills Shows you how to develop new robot behaviors by manipulating old ones and adjusting programming parameters Provides examples of programming for object seeking object avoidance decision making and much more Leads you to advanced strategies for designing your own behavior based systems from scratch Introduces the history and theory behind behavior based programming Requires no background in either programming or robotics

Theory of Automatic Robot Assembly and Programming Bartholomew O. Nnaji,1993 Machines will

gradually become programmed using computers which have the knowledge of how the objects in the world relate to one another This book capitalizes on the fact that products which are manufactured can be designed on the computer and that information about the product such as its physical shape provide powerful information to reason about how to develop the process plan for their manufacture This book explores the whole aspect of using the principles of how parts behave naturally to automatically generate programs that govern how to produce them The last decade saw tremendous work on how machines can be programmed to perform a variety of tasks automatically Robotics has witnessed the most work on programming techniques But it was not until the emergence of the advanced CAD system as a proper source of information representation about objects which are to be manipulated by the robot that it became viable for automated processors to generate robot programs without human interface It became possible for objects to be described and for principles about how they interact in the world to be developed The functions which the features designed into the objects serve for the objects can be adequately represented and used in reasoning about the manufacturing of the parts using the robot This book describes the necessary principles which must be developed for a robot to generate its own programs with the knowledge of the world in the CAD system

Designing Robot Behavior in Human-Robot Interactions Changliu Liu, Te Tang, Hsien-Chung Lin, Masayoshi Tomizuka, 2019-09-12 In this book we have set up a unified analytical framework for various human robot systems which involve peer peer interactions either space sharing or time sharing or hierarchical interactions A methodology in designing the robot behavior through control planning decision and learning is proposed In particular the following topics are discussed in depth safety during human robot interactions efficiency in real time robot motion planning imitation of human behaviors from demonstration dexterity of robots to adapt to different environments and tasks cooperation among robots and humans with conflict resolution These methods are applied in various scenarios such as human robot collaborative assembly robot skill learning from human demonstration interaction between autonomous and human driven vehicles etc Key Features Proposes a unified framework to model and analyze human robot interactions under different modes of interactions Systematically discusses the control decision and learning algorithms to enable robots to interact safely with humans in a variety of applications Presents numerous experimental studies with both industrial collaborative robot arms and autonomous vehicles

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