



A BIOLOGICAL INSPIRED COGNITIVE MODEL OF MULTI-SENSORY JOINT ATTENTION IN HUMAN ROBOT COLLABORATIVE TASKS

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Background







Different attention computational models *

Few are addressing cooperative task

Neglecting the mutual presence

- N. Pfeiffer-Lessmann, T. Pfeiffer and I. Wachsmuth, "An Operational Model of Joint Attention--Timing of the Initiate-Act in Interactions with a Virtual Human,".
- A. Frischen, A. Bayliss and S. Tipper, "Gaze Cueing of Attention: Visual Attention, Social Cognition, and Individual Differences"





Our Research Goals







ASSESSMENT DURING ATTENTION PROCESS CONSIDER THE MUTUAL PRESENCE

COMPARE THE BEHAVIORS





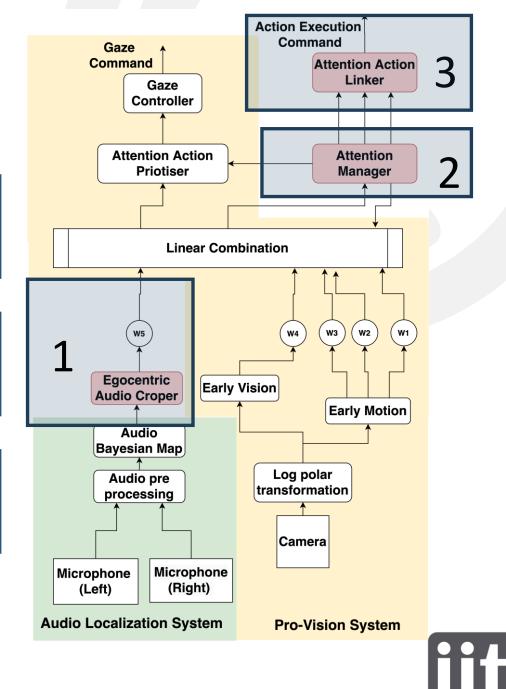
OUR CONTRIBUTION

Integration (Audio + Visual)

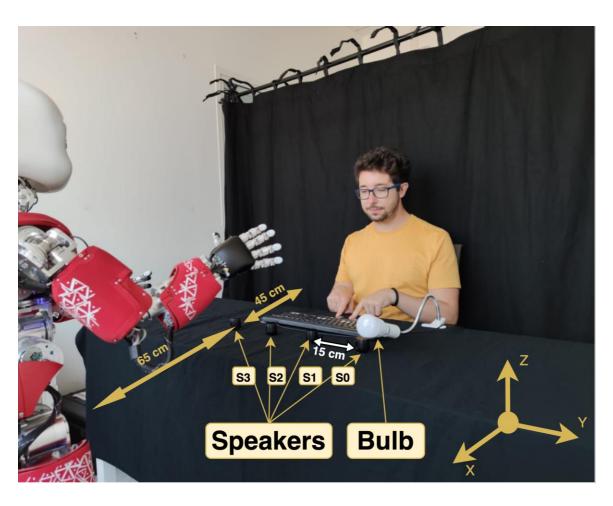
Acyclic extraction of a saliency (hot Point)

Retinotopic response projection into allocentric spatial representation





THE EXPERIMENT



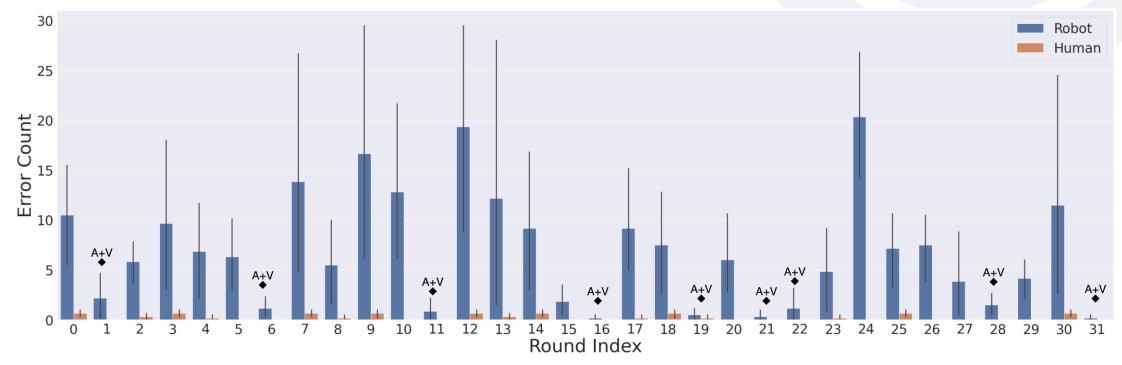
- Stimulation
 - 3 location Audio only
 - 1 location Audio + visual
- Temporal Stimulus
 - 240 Hz audio signal
 - Blue color
- Running the experiment
 - 6 subjects
 - 32 rounds each
 - 10 sec. on / 10 sec. off





RESULTS (ERROR COUNT)

- Compared error count between the human and the robot in A+V trials
- Significant deference in audio only trials

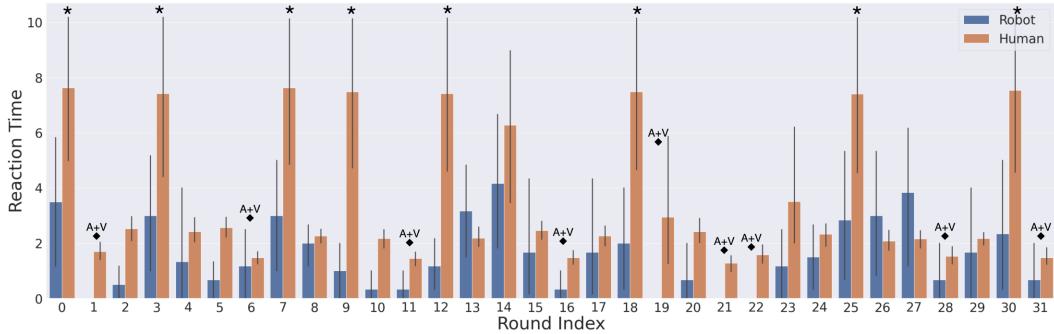






RESULTS (REACTION TIME)

- Wide Variability in RT for the robot
- Compared RT in avarage
- The robot isn't as accurate as the human

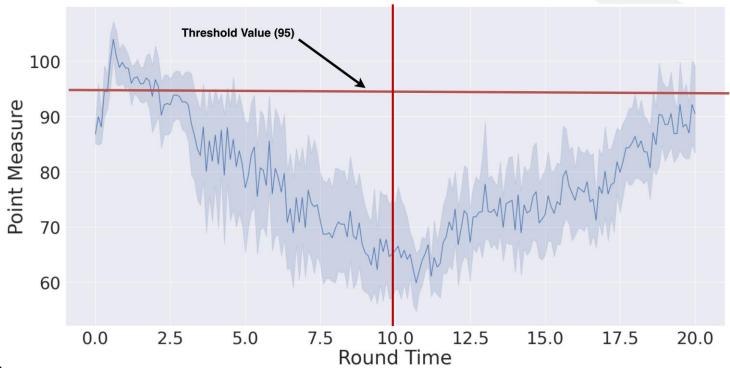






RESULTS (HOT POINT MEASURE IN A+V)

• Swift increase when the stimuli is presented

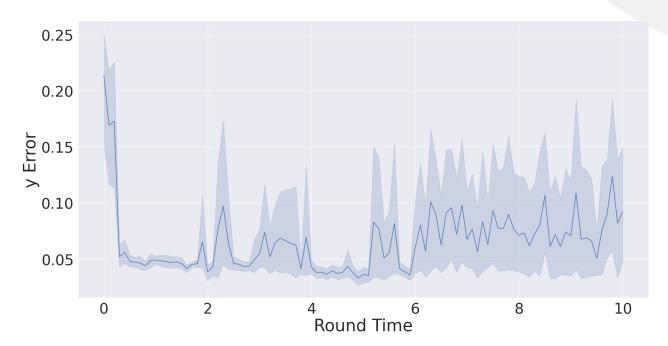






RESULTS (LOCATION ERROR IN A+V)

- Error drop when the stimuli is presented
- < 0.1 error in most of the on time on average
- Error rise again when the stimuli is off







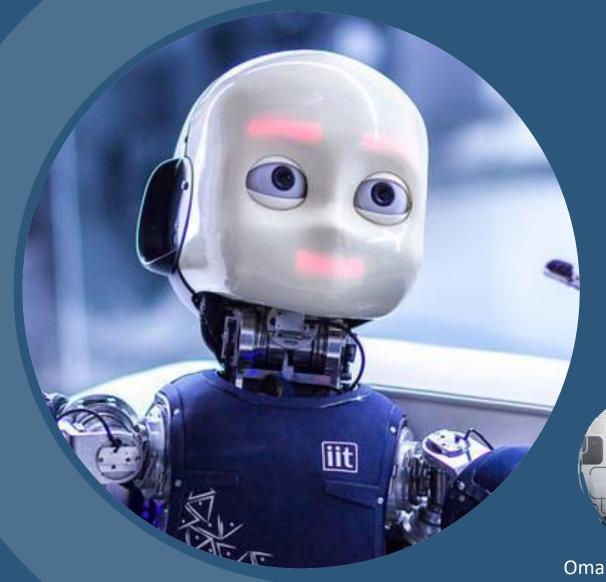
CONCLUSION

- Importance of joint attention
- It is dificult task for the robot
 - Reaction time
 - Localization accuracy
- Comparable robot and human performance when Auditory and visual stimuli is presented
- localizing the auditory stimuli is challenging









THANKYOU!



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