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Choosing a Social Robot by Understanding Human-Robot Interactions

Moolpani Deepak Inder
SSt College of Arts and Commerce, Maharashtra, India
Email: deepak.moolpani@sstcollege.edu.in

Abstract

Recent advances Science and technology led to development use Robots inside many applications in all fields of human life. Investment in the robotics sector increases human-robot interaction by bringing a variety of robots to the consumer market. Consumers frequently struggle because they have different expectations and little domain knowledge. Choose a robot. This article provides a design overview of HRI for consumers and discusses a general block diagram for HRI in the context of social robotics. It informs customers about important variables to take into account when choosing a robot and aids in the development of a standard lexicon of technical jargon. They will find the choosing process to be quick and simple. Using a fuzzy inference engine, multi-criteria decision making (MCDM) explains how to employ factors extracted from the block diagram. The authors of the article used it MCDM method to determine the seniority of the city of Vilnius, the most expected future development of these neglected areas. Its result is confirmed by expert investigation and COPRAS method. Pepper is in highest value Paro is in lowest value.This paper provides to develop Cognitive, Collaborative Humanoid Robots. People understand each other socially, It allows Engaging Communication, social learning, and cooperation are just a few examples of the intricate social interactions that people engage in. We offer our theoretical foundation, a new Compare the collective Purpose theory and situated learning theory, and we Prove is structure used create our friendly the humanoid robot, Leonardo. We show the robot capability quickly and efficiently learn conversation, collaborate with human to perform the learned task. Many new and exciting applications for robots must be addressed in order it should it plays argues for the use of Cognitive Developmental Robotics (CDR) as a fresh design theory for humanoid robots. This idea might provide explanations for human behaviour that go beyond those provided by the scientific and social sciences. Additionally, because humanoid robots have numerous sensory modalities and must address scaling issues that are sometimes overlooked in simple domains, they demand systematic emphasis in the design of artificial creatures.

Keywords: MCDM,Aibo, Aeolus, Buddy and Nao.

1. Introduction

Dirty, dull and dangerous—robots are doing it for years regardless of them. But as progress increases, robots engage in more complex and non-ethical activities. According to According to the International Federation of Robotics (IFR), robots will soon change a companion human's daily life as they quickly transition from industrial applications to less regimented private situations. According to experts, social robotics is a relatively new and developing area. This requires Multidisciplinary approach, in which robot design and methodology relies in contributions from a variety of fields, including design, artificial intelligence, human factors, social and cognitive science, and more. Final goal A social robot creates interesting, Natural and effective interactions between robots and humans by creating social mechanisms for understanding and communication. This view is opened the door to a field of study known as human-robot interaction (HRI). Social sciences, computer science, electronics, engineering all converge at HRI. The basic objective HRI is to be understood, perceive evaluate human/robot systems. Broadly speaking, think of it as HRI the protocols for building, programming, testing, debugging and reprogramming robots. There are different types Robots in the market and not each robot is suitable/designed for each task. Choosing an Influenced by a robot for a specific task many such as cost, autonomy, performance etc. Typically, the understands the customer's needs and helps identify and select the robot. The response of a given robot is not as described by the seller and no fulfills its reason. This leads to an incorrect incompetent selection a robot that meet the customer's expectations. The only that day the Sales Representative Recommendations; He/she should be aware is considered selecting a suitable social (assistive) Robot. This article talks about it issue helping the customer feels the various choosing a robot as per the customer's need/need without missing out on any important aspect. Also, this reduces the chance of getting lost key criteria, leading for better selection the robot. Finally, an MCDM is a COBRAS method to prove use Derived criteria a generic block diagram. Pepper in highest value Paro is in lowest value.

2. Knowing Your Robot

Additional I compared options to Kanab chin. People frame different People from diverse origins, cultures, sectors, etc., have varying demands and expectations for them. Given Investment and growth of start-ups the fields of robotics. Drawing the common will help consumers (students, housewives, seniors, researchers, etc.) develop a common technical vocabulary related to social robots Is it the marketplace? The key concept of the map Make consumer robot selection more orderly and effective by breaking the entire process into different blocks/layers and providing to consider each level. A healthy HRI is essential for consumer benefit robot use. To achieve user-friendliness/interaction quality in robots, HRI research should focus "social interaction" "aesthetic" "functional" elements. Therefore, this block diagram provides an Overview of HRI's design hobbyist and Consumer-centric social robots. A is made up of six different building blocks or layers. Different aspects of the problem domain are taken care of via domain analysis. This thoroughly encompasses concept design. Recognize the application setting (such as a house, business, hotel, etc.) and determine whether or not the robot is usable. At this stage thinks about the final environment in which the robot will be positioned, Used by designers and researchers different etc environmental investigation, participatory design, development. This metaphor "intelligence requires a body and environment," and its types are anthropomorphic, zoomorphic, caricature, and functional. Mainly social robots take forms, namely anthropomorphic (human-like) or anthropomorphic (like an animal). Mainly social robots have forms, human form (human-like) or animal (animal-like) as depicted in the row. Avoiding A strange valley of robots appears animated is one of the important factors for designers. Zombies, who cannot be accepted by consumers in the general public, should Search a Small and efficient robot design is Less prone to wear and tear, which ultimately reduces overall maintenance costs. Humans and robots play a variety of characters, including supervisor, operator, coworker, and spectator envisions the ecosystem. In terms of sensor selection, sensors are the robot environment. Data from various such as hop tick, Triangular axis, sight and sound, space and range, temperature and gas, torque are sent for units that process data to extract it attributes that are specific to a given sensor, such as its range, accuracy, sensitivity, and power usage. Must the consumer to search built-in Sensors in the robot that help them complete tasks in their chosen environment. Learning and processing use the communication and work model modules to generate control signals that carry out the desired task. Additionally, it makes use of several computer approaches, including neural networks, artificial intelligence (AI), and optimization methods. Improve the robot's learning to perform social-cognitive capabilities into social robots that enable And they learn interact in a human-centered environment, whereas consumer factors should be sought such as Is the robot based on AI/DL (learning) when choosing a robot error-correcting ability) or task-specific. Ultimately, robotics has great potential to simplify and streamline human life. Robotics will human daily life of Robotic applications It promises a new era in man life, which significant in Time labor. According to Projections indicate that there will be 7.4 million robots used wide. 2 billion USD markets, which enables the introduction of robots at global platforms such as the and Market Availability, portrays currently available social robots based on popularity and others innovative Features. The table contrasts the robots based on the characteristics, basic shape, moving accessories, autonomy, and learning capacity that were previously discussed. Moving components indicate movable it Robot, whereas autonomy refers to autonomous movement determining. Complementary learning skills include the ability to recognize faces, remember previous interactions with humans, and act accordingly.

3. Selecting Your Robot

There are many different kinds of robots on the market, and not every robot is suitable or designed for every task. Because of this, it is important to make a multi-criteria decision that considers available options as well as customer satisfaction.These criteria result Understanding design perspective the HRI process in social robotics (in general). It helps to realize the various aspects (illustrated in the generalized block diagram) of selecting the robot as per the customer's need/requirement without missing any important aspect. Since there are many parameters to select a robot requires A multi-criteria decision-making system select the appropriate robot, here a machine-based ranking system is proposed. A companion robot was domestic environments to show companionship with humans and animals performs various tasks such as escapism, safety, chat, and assistant To put it another way, a companion robot is combination Smartphone is a pet and the best features of A vacuum cleaner has different users may a needs, may lead different criteria selection. Among the eight criteria, namely form the positive qualities include autonomy (C7), communication (C8), learning ability (C5), customization and programmability (C6), perception and characteristic (C3), and battery backup (C4). (the best of these criteria are) and cost (C2)) an ineffective criterion (because the customer wants the lowest price). In this paper, Fuzzy COPRAS method is used determine relative importance criteria and clarity of various criteria.

4. MCDM Method

After conducting an analysis of various multivariate estimation methods, the authors further use the COBRAS method. The COPRAS system was developed by Vilnius Ked Minas University of Technology scientists Zavatskas and Kalkaska's and first published in their respective article. The essential principle of the method lays in the possibility of combining the ridge values of all indicators of R qualitative account, that is, the value of the method criterion. Calculations based on COPRAS method are performed using classical normalization. Different MCDM methods are used for different decision making process. Complex proportionality Rating (COPRAS) is one of the most popular and commonly used The MCDM approach was Zavatskas Kalkaska's. It is used to rank alternatives based on that that multiple Criteria used relative criterion the utility of alternatives. The Best choice alternative done Taking into consideration best resistance solutions. Click here to download COPRAS, Live and Manuscript. A criteria system and criteria values and weights that define alternatives efficiently COPRAS has several advantages than Other MCDM methods estimation Mixed data (COPRAS), regularization, shorter computation time, more simple and transparent computation process. Prioritization by Unity COPRAS rank alternatives by considering their effect on cost and benefit-type criteria within an Evaluation process. Additionally, there may be cobras adopted easily by anyone Decision problems of interest. An important advantage of doing COPRAS is superior to other MCDM methods utility of alternately, as a percentage; the degree ran the alternative compares favourably or negatively to other alternatives. This knowledge will Useful making. Additionally, recent research results show that COPRAS provides.

5. Analysis and Discussion

C1, C2, C3, C4, C5, C6, C7, C8 it is found that Pepper is showing the highest value for Paros is showing the lowest value. Poor consumer perception on recycled materials it is seen that Pepper is showing the highest value for Paros is showing the lowest value. Poor supplier commitment it is seen that Pepper is showing the highest value for Paros is showing the lowest value. Poor success of curbside pickup it is seen that Pepper is showing the highest value for Paros is showing the lowest value.

TABLE 1. Choosing a Social Robot by Understanding Human-Robot Interactions

	C1	C2	C3	C4	C5	C6	C7	C8
Aibo	0.0185	0.2472	0.0705	0.0176	0.0823	0.0141	0.1164	0.0635
Aeolus	0.0412	0.0824	0.0529	0.0176	0.0882	0.0141	0.1164	0.0564
Buddy	0.0412	0.2884	0.0661	0.0498	0.0294	0.0211	0.1099	0.0564
Nao	0.0396	0.1442	0.0705	0.0147	0.0882	0.0635	0.0918	0.0529
Einstein	0.0370	0.3708	0.0352	0.0235	0.0117	0.0141	0.0129	0.0564
Pepper	0.0656	0.0824	0.0352	0.0529	0.0940	0.0635	0.1164	0.0656
Vector	0.0185	0.3584	0.0441	0.0117	0.0235	0.0141	0.0388	0.0458
Paro	0.0211	0.2060	0.0529	0.0352	0.0117	0.0141	0.0129	0.0599
Lynx	0.0396	0.3048	0.0705	0.0117	0.0705	0.0352	0.0918	0.0529

Table 1 shows the Choosing a Social Robot by Understanding Human-Robot Interactions using COPRAS method for Alternative: Aibo, Aeolus, Buddy,Nao, Einstein,Pepper, Vector, Paro, and Lynx.Evaluation Preference: C1, C2, C3, C4, C5, C6, C7, C8.

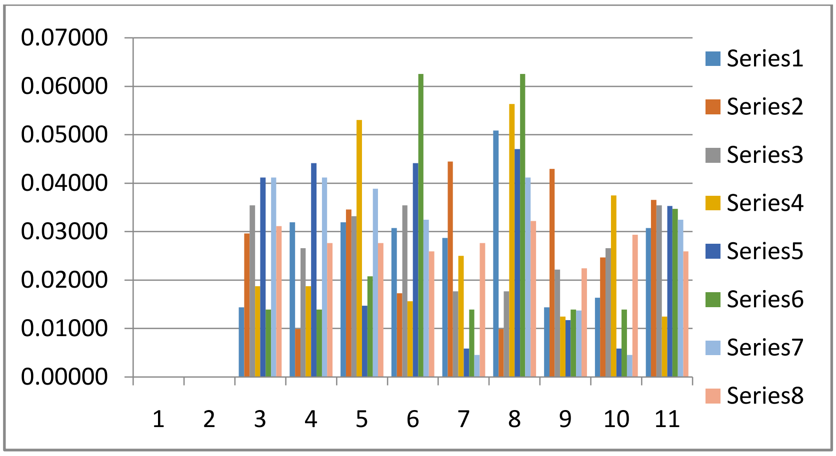

FIGURE 1. Choosing a Social Robot by Understanding Human-Robot Interactions

TABLE 2. Normalized Data

Normalized Data							
C1	C2	C3	C4	C5	C6	C7	C8
0.0574	0.1186	0.1416	0.0750	0.1648	0.0556	0.1646	0.1246
0.1278	0.0395	0.1062	0.0750	0.1766	0.0556	0.1646	0.1106
0.1278	0.1383	0.1328	0.2122	0.0589	0.0831	0.1554	0.1106
0.1229	0.0692	0.1416	0.0626	0.1766	0.2502	0.1298	0.1038
0.1148	0.1779	0.0707	0.1001	0.0234	0.0556	0.0182	0.1106
0.2035	0.0395	0.0707	0.2254	0.1882	0.2502	0.1646	0.1287
0.0574	0.1719	0.0886	0.0499	0.0470	0.0556	0.0549	0.0898

0.0655	0.0988	0.1062	0.1500	0.0234	0.0556	0.0182	0.1175
0.1229	0.1462	0.1416	0.0499	0.1411	0.1387	0.1298	0.1038

Table 2shows the normalized data which is calculated from the data set each value is calculated by the same valueon the table 1. Choosing a Social Robot by Understanding Human-Robot Interactions divided by the sum of the column of the above tabulation.

TABLE 3. Weightages

Weightages							
0.25	0.25	0.25	0.25	0.25	0.25	0.25	0.25
0.25	0.25	0.25	0.25	0.25	0.25	0.25	0.25
0.25	0.25	0.25	0.25	0.25	0.25	0.25	0.25
0.25	0.25	0.25	0.25	0.25	0.25	0.25	0.25
0.25	0.25	0.25	0.25	0.25	0.25	0.25	0.25
0.25	0.25	0.25	0.25	0.25	0.25	0.25	0.25
0.25	0.25	0.25	0.25	0.25	0.25	0.25	0.25
0.25	0.25	0.25	0.25	0.25	0.25	0.25	0.25
0.25	0.25	0.25	0.25	0.25	0.25	0.25	0.25

Table 3 shows the weight of the weight is equal for all the value in the set of data in the table 1. The weight is multiplied with the previous table to get the next value.

TABLE 4. Weighted normalized decision matrix

Weighted normalized decision matrix							
0.01	0.03	0.04	0.02	0.04	0.01	0.04	0.03
0.03	0.01	0.03	0.02	0.04	0.01	0.04	0.03
0.03	0.03	0.03	0.05	0.01	0.02	0.04	0.03
0.03	0.02	0.04	0.02	0.04	0.06	0.03	0.03
0.03	0.04	0.02	0.03	0.01	0.01	0.00	0.03
0.05	0.01	0.02	0.06	0.05	0.06	0.04	0.03
0.01	0.04	0.02	0.01	0.01	0.01	0.01	0.02
0.02	0.02	0.03	0.04	0.01	0.01	0.00	0.03
0.03	0.04	0.04	0.01	0.04	0.03	0.03	0.03

Table 4 shows the weighted normalization decision matrix it is calculated by multiplying the weight and performance value in table 2 and table 3.

TABLE 5. Bi & Ci & Min(Ci)/Ci

	Bi	**Ci**	**Min(Ci)/Ci**
Aibo	0.194	0.031	0.7213
Aeolus	0.186	0.028	0.8121
Buddy	0.227	0.028	0.8121
Nao	0.238	0.026	0.8658
Einstein	0.140	0.028	0.8121
Pepper	0.286	0.032	0.6982
Vector	0.131	0.022	1.0000
Paro	0.129	0.029	0.7646
Lynx	0.218	0.026	0.8658

Table 5 shows the value of Bi, Ci, Min(Ci)/Ci The Bi is calculated from the sum of the Alternative: Aibo, Aeolus, Buddy,Nao, Einstein,Pepper, Vector, Paro, and Lynx. The Ci is calculated from the sum formula used.

TABLE 6. Qi & Ui

	Qi	**Ui**
Aibo	0.219	70.7769
Aeolus	0.214	69.1754
Buddy	0.255	82.3679
Nao	0.268	86.5425
Einstein	0.168	54.2549
Pepper	0.309	100.0000
Vector	0.165	53.4511
Paro	0.155	50.2582
Lynx	0.247	79.8588

Table 6 shows the Qi & Ui & value Qi sum, minimum formulas using this table.

TABLE 7. Rank

	Rank
Aibo	**5**
Aeolus	**6**
Buddy	**3**
Nao	**2**
Einstein	**7**
Pepper	**1**
Vector	**8**
Paro	**9**
Lynx	**4**

Table 7 shows the final result of this paper the Aibo, is in 5 th rank, the Aeolus is in 6 th rank, the Buddy is in 3 rd rank, the Nao is in 2 nd rank the Einstein is in 7 th rank the Pepper is in 1st rank the Vector is in 8th rank the Paro is in 9th rank tand Lynx is in 4th rank.The final result is done by using the COPRAS method.

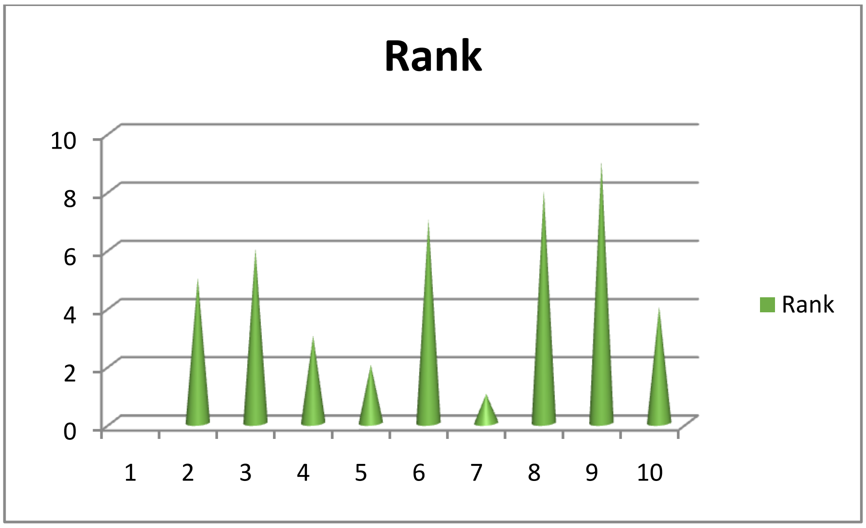

FIGURE 3. Rank

Figure 3 shows the graphical view of the final result of this paper the Aibo, is in 5 th rank, the Aeolus is in 6 th rank, the Buddy is in 3 rd rank, the Nao is in 2 nd rank the Einstein is in 7 th rank the Pepper is in 1st rank the Vector is in 8th rank the Paro is in 9th rank tand Lynx is in 4th rank. Pepper is in highest value Paro is in lowest value.

6. Conclusion

Looking it is clear that in the future, robots working alongside humans they are going to play an important Stock society. Success for an efficient and precision a robot system is one of interactions robot. This article compares some of the social robots in the world today. A general block diagram to understand the HRI process for selecting the relevant robot is given in this article. It provides a design perspective social robots and HRI narrows down various selection parameters. It helps the new customer to understand and interact with various technical parameters; the robot makes the easy useful for them. Finally, MCDM is a COBRAS method that uses a fuzzy inference engine for Ranking Different social robots. Recent advances led in science and technology creation use Robots inside many Applications in human life. Robotics investments bring robots to the area, increasing human-robot interaction. Consumers who have different needs frequently struggle Choose a robot. This article provides a design overview of HRI for customers and discusses a general HRI in the context of social robotics. It is helps will grow a common Glossary of technical terms and information them of key factors to consider when choosing a robot. The selection process will be easy and efficient for them. Multi-Criteria Decision Making (MCTM) Fuzzy inference done with the help of the machine explain the use of factors derived from the block diagram. The authors of the article used it MCDM method to determine the senior part of the city of Vilnius, in which the future development of neglected areas was most expected. Its result is confirmed by expert investigation and COPRAS method.Pepper is in highest value Paro is in lowest value.

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