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Sharing Spaces with Robots
An Integrated Environment for Human-Robot Interaction

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ABSTRACT
In this paper we offer an intelligent integrated environment for human-robot interaction. This environment takes advantage of the fact that robots are both digital and physical entities, thus improving human-robot interaction and communication. Using mixed reality, our approach brings digital information directly into the physical environment, allowing users to interact with robots’ ideas and thoughts directly within the shared physical interaction space. We also present a taxonomy which we use to organise and classify the various interaction techniques that this environment offers. Using this taxonomy, we demonstrate by detailing three interaction techniques, thought crumbs, decorations and bubblegrams. To evaluate these techniques, we offer the design of a realisable prototype.

Categories and Subject Descriptors

Keywords
Intelligent Environment, Mixed Reality, Human-Robot Interaction

1. SCENARIO
A futuristic human and robot collaborative search and rescue team has been dispatched to assist in a situation concerning a burning apartment building. En route, the robot team members analyse a map of the burning building, calculating things such as potential danger areas, likely civilian locations, and efficient ways to distribute the team throughout the building. At the same time, the human team members prepare and put on their protective gear, including a helmet which has mixed reality capability. This capability is used to augment the vision and hearing of the human team members with information from the robot team members.

As the team enters the building, the humans quickly follow highlighted mixed reality paths representing the robots’ suggested routes. As the search progresses, additional highlighted paths are created, representing which route each robot has taken. If a robot hits an obstructed door or encounters dangerous heat levels, it attaches mixed reality icons to the environment, placing a locked icon on the door or heat symbols on the walls. Human members who later come the same way see these icons and use the information to make decisions. When human and robot team members meet, the robot pops up a mixed reality menu interface to show its current status and to ask for further instructions.

2. INTRODUCTION
Robot technology is advancing steadily, and many people believe that, similar to the computer revolution over the last few decades, a robotics revolution is upon us[11, 13]. Indeed, Norman[13] suggests that we are already surrounded by robots, such as computerised dishwashers and cars, but they currently lack the intelligence and capability required for us to see them as such. As robots become increasingly intelligent and capable, we will find ourselves sharing our environment with them in many ways. As such, it is important that we understand the various issues and problems surrounding interaction with robots and develop effective interfaces to work with them. This field of study is called human-robot interaction (HRI)[8].

Robots are a class of computers which are distinguished by their presence in the physical world. Unlike a conventional computer which is primarily a digital entity, a robot is both a physical and a digital entity, simultaneously perceiving, functioning and interacting in both the digital and physical realms. Current human-robot interfaces often fail to acknowledge this, and are commonly designed using physical modalities such as speech-based interfaces or digital modalities such as remote control software tools. This separation of interaction spaces can hinder communication between humans and robots, resulting in various interaction problems such as limitations in conveying information or inefficiencies due to issues in input/output unification[4, 18].

One solution to this problem is to use mixed reality (MR) as an interaction paradigm. MR is a technique which tracks components of the physical world and augments them with...
useful computer data. This is commonly accomplished by projecting augmented images onto the user's environment or by using a head-mounted display (HMD) to synthetically augment the vision of the wearer[1]. We believe that MR solves the interaction problems mentioned above by allowing the robot to superimpose digital information directly onto the physical environment, allowing a human user to interact with the digital information directly within their physical interaction space. Combining the physical and MR interaction spaces, we have devised an intelligent environment which the humans and robots can use to interact. We call this human-robot environment the MR Integrated Environment (MRIE)\(^1\).

Given that robots are generally autonomous and mobile, they have a very large and dynamic physical interaction space. With the MRIE, we offer an environment which allows robots to utilise this space both physically and digitally, using the entire physical environment as their digital interaction space. The result of this is an extremely flexible interaction environment which robots can use to express their digital ideas and thoughts. We believe that this environment also aids in increasing a human's awareness of the robot, which some researchers claim improves understanding of the robot's location, identities, and activities[20].

There is a wide range of potential human-robot interaction techniques within the MRIE. As a method of organising this, we introduce a taxonomy of the MRIE which we use to analyse, classify, and compare various MRIE interaction techniques. This taxonomy maps the MRIE into four variables: virtuality, lifespan, ownership, and activity. We also introduce the interaction field, a concept where each variable of the taxonomy represents an axis in a four dimensional field of interaction techniques. To demonstrate the application of this taxonomy and to show how various techniques fit into the interaction field, three MRIE interaction techniques (thought crumbs, decorations and babblegrams) are presented. Furthermore, we detail the design for a preliminary prototype which will be able to realise and evaluate the ideas and techniques presented here.

3. RELATED WORK

Mixed reality (MR) has been used as a means of combining digital information with the physical world for various applications, including animating storybooks (the MagicBook project)[1], controlling robots [4, 9, 14, 17], modelling volumetric data [7, 16], and assisting with medical surgery[5]. Work by Ramesh et. al. has also discussed using MR to create an integrated environment (shared between humans) rather than particular techniques[15].

From a simple perspective, most MR techniques can be classified as either using head-mounted-display (HMD) visualisation or projective visualisation. HMD visualisation offers portability and flexibility, given that they are often light weight and can be connected to a wearable computer, and that they can display anywhere within the user’s vision. However, HMDs often constrict the user’s vision due to a poor field-of-view and low resolution, resulting in hand-eye coordination issues and possibly motion sickness. Projective visualisation, on the other hand, can be integrated seamlessly into a user’s entire field of view, allowing the user to use the full capabilities of their natural vision. The downside, however, is that projectors are generally less portable and flexible than HMDs, as projectors are often heavy and difficult to move and they require a projection surface and appropriate lighting.

As shown here, MR offers a wide range of interaction techniques and ideas. To organise this range, there has been work on describing, organising, and mapping the diverse MR interaction space. Milgram and Kishino map MR interaction to a set of criteria which is visualised on the virtuality continuum[10], a one dimensional axis which classifies systems as somewhere between the pure physical environment and a complete virtual environment. Others have expanded on the virtuality continuum, such as Dubois et. al. who covers the entire continuum, offering a clear mechanism for discussing interaction techniques[2]. The virtuality continuum provides a mechanism for classifying MR systems and techniques. For example, the MagicBook project mentioned above used this as motivation and to explain the various interaction techniques integrated into the system[1].

The literature offers various taxonomies, including ones that target general human-computer interaction[12], and ones that are more HRI-specific[4]. For example, Yanco and Drury offer a taxonomy for multi-robot systems which uses task type and criticality for classification[20].

While mixed reality has been used for various interaction applications, there has been a limited amount of work using mixed reality for human-robot interaction (HRI). In relation to this work, our MRIE is unique in that it offers an integrated digital and physical environment to be shared between humans and autonomous robots. We also offer a taxonomy for the MRIE, similar to other taxonomies offered, and the concept of the interaction field. The interaction field builds on Milgram’s virtuality continuum, providing a multi-dimensional mechanism for classifying MRIE interaction techniques; the virtuality continuum is simply a single axis within our four-dimensional interaction field, which we present later. Just as Milgram’s taxonomy of mixed reality and virtuality continuum offer a clear way to analyse, classify, and compare various MR interaction systems, our taxonomy and interaction field offer similar benefits for analysing MRIE interaction techniques.

Because the MRIE deals primarily with humans interacting with autonomous and mobile robots in a shared physical space, portability and flexibility are very important aspects of prototype plan. As such, our prototype plan uses HMDs for the mixed reality interface.

4. A TAXONOMY FOR THE MIXED REALITY INTERACTION ENVIRONMENT

Our taxonomy maps the entire interaction space of the Mixed Reality Integrated Environment (MRIE) into four key variables, lifespan, ownership, activity, and virtuality, providing criteria which we use to describe existing MRIE interaction techniques and to construct new ones. The MRIE provides many possibilities, where both humans and robots can create, modify, destroy, and interact with MR elements.

\(^1\)pronounced merry
An interaction technique in the MRIE can be broken down into separate physical and MR components; the physical component can include instances such as touching a robot or working together with a robot to push a physical object, and the MR component can include any interaction which makes use of the mixed reality interaction paradigm. While our taxonomy covers all MRIE interaction techniques, our focus will be on using the taxonomy to analyse the capabilities offered by the mixed reality aspects.

4.1 Lifespan
The lifespan variable determines how long instances of a MRIE interaction technique last. For example, a robot may place a permanent MR element into the environment for information purposes, resulting in an arbitrarily long or permanent lifespan. On the other hand, a robot may display a surprise mark which is designed to disappear soon, resulting in a very short lifespan. Lifespan can also be connected to an event in the environment or a variable on the owner, so that the interaction instance ends when the event is triggered.

Another option here is to have the lifespan of an instance tied to an event in the environment or to a variable on the owner of the instance, so that the instance ends when the event is triggered.

4.2 Ownership
The ownership variable determines which robot in the MRIE, if any, owns the technique instance; ownership reflects who has the control of the instance. This variable also includes partial ownership by other entities in the environment. For example, entities in the environment may have control to alter instances owned by a different entity. The possibilities here resemble common file system permissions, where the owner robot can decide which other entities can view or edit aspects of a technique instance. This allows for private interaction between two entities or a group, where entities not involved would not be able to perceive or be involved in the interaction. Instances can also have no owner, such as MR element left at a location for information purposes; any element in the public space can perceive or modify these public instances.

4.3 Activity
The activity variable determines how active an interaction technique instance is. This includes the level at which the instance attracts attention, in what way the instance uses the representation techniques, as well as how it responds to attention or direct interaction. An example of a technique with very low activity is a MR element which displays a static decoration on a wall; this technique does not actively invite attention, and does not react to interaction attempts. A variation on this technique which uses animation or other methods to gain attention would have a higher activity level. An example of a technique with high activity is a MR interactive menu system which incorporates three dimensional animation and sounds for interaction purposes. Upon creation, this menu could make a popping noise to notify the user of its creation, and could react richly to a user’s interaction. Activity may also be dependent on the ownership or lifespan variables, so that a technique instance reacts differently for different users or as it ages.

4.4 Virtuality
The virtuality variable is based on Milgram’s virtuality continuum[10]; it categorises the representation technique as somewhere between purely physical and purely virtual. For example, a purely physical technique could involve physically touching a robot and getting a physical action response, while a purely virtual technique could be to use virtual reality to control a robot. Most techniques possible in the MRIE, however, lay somewhere in the middle. For example, a MR interactive menu which pops above a robots head has physical elements in that it is integrated into the physical space, and has virtual elements since the menu is presented using virtual means. Note that virtuality includes all forms of virtual information, including graphics and sound. An example of a technique which uses both aural and visual representations is a MR sign which visually wobbles while producing a cranking sound to show that it is loose.

4.5 Interaction Field
The interaction field is a conceptual representation of our taxonomy, where each variable of the taxonomy, ownership, timespan, activity, and virtuality, represents an axis in a four dimensional field of interaction techniques. Any MRIE interaction technique can be either a point in the field, or span a subspace of this field. The interaction field offers a four-dimensional representation of our taxonomy, very much like how Milgram’s one-dimensional virtuality continuum offers a representation of his taxonomy of mixed reality.

5. INTERACTION TECHNIQUES
The MR Integrated Environment (MRIE) provides a flexible interaction environment between humans and robots which can be used to simultaneously interact in the digital and physical realms. Within this environment, the various interaction techniques can be described using our taxonomy of the MRIE. This section illustrates both the possibilities of the MRIE interaction space and the use of our taxonomy by introducing and discussing example interaction techniques.

There is a large number of possible interaction techniques in the MRIE. This section presents three different techniques, illustrating how the MRIE can be used, and how techniques can be described using our taxonomy. These techniques are bubblegrams, thought crumbs, and decorations.

5.1 Bubblegrams
Bubblegrams are MRIE interaction techniques which are based on comic-style thought and speech bubbles, with the idea that they represent a robot’s thoughts and expressions. They are primarily visual interfaces which use MR to overlay the bubbles onto the physical interaction scene, floating next to the robot which generated it. Bubblegrams can also be interactive, offering interfaces such as status displays or system menus, resembling an interactive physical display directly within the physical task space.

Lifespan: Bubblegrams are designed for short-term and specific interaction, and are generally not used for long-term tasks; they are designed to convey current information or for immediate interaction. For example, a surprise bubblegram floating over a robot’s head may last for five seconds,
and a system menu bubblegram will be destroyed as soon as the interaction is complete.

Ownership: Following the comic-style bubble motivation, bubblegrams are represented as being spatially attached to the owner in the MRIE interaction space. Furthermore, bubblegrams are used to represent a single robot’s thoughts and expressions, and so bubblegrams must have a single owner.

Activity: While interactivity is not implied by the thought bubble motivation, bubblegrams offer a wide range of activity, ranging from a static graphic with no interactivity to a full-fledged animated and interactive menu. A static graphic could be a robot displaying a cloud emblem over its head to indicate that it is depressed, and a highly interactive bubblegram can provide a wide range of data, ranging from email messages to video or picture data.

Activity of the bubblegram may change throughout time as well, such as starting out by popping into a user’s environment but becoming static after that.

Virtuality: Bubblegrams have medium virtuality, since they can actively bring complex digital data into the user’s interaction space. For example, a fully-interactive and animated bubblegram menu has medium virtuality because it brings a vast range of information including videos and audio into the user’s interaction space and allows the user to directly interact with the virtual space.

5.2 Thought Crumbs

Thought crumbs, inspired by bread crumbs from the children’s story Hansel and Gretel, is an interaction technique which uses pieces of digital information to represent a robot’s thoughts or observations. These are pieces of digital information which an entity leaves behind in the MRIE by virtually attaching them to specific physical locations. These thought crumbs are then represented by a MR element, consisting of visual and/or audio augmentation, at that particular location. For example, search and rescue robots may use thought crumbs to leave information such as air quality and temperature levels at particular locations. Thought crumbs can also be interactive, such as expanding when a user touches them to give additional information.

While we see thought crumbs as a technique to be used by robots, we acknowledge that they can sometimes also be used by human users; for example, a human may want to mark particular locations for a cleaning robot to clean.

Lifespan: Thought crumbs can have any length of lifespan that the robot wants, depending on how long the owner thinks the information will be relevant. Some thought crumbs will be given a period of time after which they will expire, while others will not expire until someone explicitly erases them. A short-lived thought crumb may be a note left by a cleaning robot after cleaning a floor to say that the floor is wet; this thought crumb would expire after approximately ten minutes. A long term thought crumb could be a set of directional arrows left by a robot to direct a flow of traffic. These arrows would possibly be left until explicitly destroyed, possibly weeks later.

Ownership: Thought crumbs, once placed, are public elements within the shared environment and have no owner. Being an independent MR element, any entity within the space has full access to modify or destroy it. This fits many of the examples already presented, as a cleaning robot may destroy thought crumbs which a human placed asking it to clean, or a human may remove thought crumb notes left behind by a cleaning robot.

Activity: Thought crumbs generally offer little to medium activity. The concept of a thought crumb is to represent basic ideas and information which a robot in the space wishes to attach to a location. As soon as the information which a robot wishes to leave at a location becomes complex or highly interactive, then thought crumbs are no longer applicable and another interaction technique should be used.
Interactive thought crumbs should only use the interaction to give basic expansions on the data already presented. An example of an interactive thought crumb could be a box which displays a bit of text, with scroll bars on the side to scroll through the text.

Thought crumbs can use a full range of representation techniques to convey their information, including three dimensional animated graphics and sound. This representation technique can be used to increase the activity of the thought crumb, trying to get the users attention. For example, in an emergency situation a thought crumb may emit a siren noise and flash bright colours. This representation can also be dependent on the age of the thought crumb, such that the age is conveyed to human users. For example, an old thought crumb may look wrinkled, faded, or rusty.

Virtuality: Thought crumbs have medium virtuality, as they actively use the virtual techniques to convey information. For example, a thought crumb may use flashing lights and animation to attempt to get a user’s attention.

5.3 Decorations
A decoration is a MIRIE interaction technique which a robot can use to decorate the MIRIE, virtually attaching MR decorations to physical locations. These decorations are intended to be personal, artistic, and relatively permanent within the MIRIE. Decorations can be used for placing MR paintings on a wall or to overlay patterns on an environment. For example, a robot may place its favourite snapshots on a wall and decorate a room based on some observations that it found interesting. A human user could then view this space, getting insight into the personality of the robot. Decorations are primarily for an entity’s own expression, as they are designed for personalisation.

Lifespan: Decorations are persistent MR elements which do not have a specified lifetime. This means that they exist until explicitly destroyed by the owner. This is because decorations are not likely to change relatively fast, and by their very nature they are intended to be static.

Ownership: Decorations are owned solely by the robot creator, since they are personal MR elements. This means that other entities in the MIRIE can not edit or destroy the decoration. Furthermore, the owner has full control of who views the decoration; some decorations may be visible by the owner only, while others may be visible by a group of friends only, or by everyone.

Activity: Decorations generally have low activity. They have no direct interactive properties; as the name suggests, they are designed for decorating an environment, and have no direct utility which an interaction system could take advantage of. However, decorations can use any of the representation methods available, including the full range of graphic and audio augmentation. This allows a level of flexibility in what the owner of a decoration can represent with it. Furthermore, the representation of the element can be dependent on variables in the owner, such as the owner’s mood or how busy the robot is. For example, a portrait decoration may reflect the mood of the decoration’s owner, smiling when the robot owner is happy or frowning when the robot owner is sad.

Virtuality: Decorations have medium virtuality. This is because decorations can use animations and graphics to bring digital information into the MIRIE.

5.4 Applications
The three MIRIE interaction techniques presented in this section provide a multitude of possibilities and can be used in various situations. This section is used to illustrate possible uses and to motivate the MIRIE interaction space. Two application scenarios are discussed: interaction with search and rescue robots, and interaction with a household robot.

5.4.1 Search and Rescue
Although this scenario has already been presented, a variant is expressed here in terms of the three introduced interaction techniques.

Imagine a futuristic human and robot collaborative search and rescue team which uses the MIRIE as a versatile and dynamic interaction environment. As the team enters a burning building, the robot team members rush ahead, surveying the building and leaving behind MR thought crumbs. These thought crumbs augment the vision of the humans, suggesting routes to take and highlighting various observations along the way. These observations include locked icons on doors which the robots found to be obstructed or skull and cross-bone poison icons representing dangerous gas levels. Finding a human survivor or victim, a robot notifies the human team members, and the humans can follow the particular robot’s thought crumbs directly to the person.

Upon encountering a human team member, a robot can display a bubblegram to the human, popping up a MR system menu which can be used to get status information about the robot or to give the robot commands. Humans can also issue queries to the robot, to get information about other robots or vital signs of a survivor, and will receive live results in an active bubblegram. In this scenario, humans can also leave thought crumbs behind for other humans or robots. For example, a human may want to leave information to other
team members, leave directions for any robot which comes their way, or to mark a spot where capable robots should bring victims and survivors.

This scenario does not use the decorations interaction technique because of the nature of the scenario. Decorations are for long-term static elements, whereas the search and rescue team will not likely frequent the same rescue locations.

5.4.2 Household Robot
Household robots exist on the market today, and with advancing technology they will likely become more popular. As such, effective HRI interaction techniques will become increasingly important.

Imagine a household robot which does cleaning and basic chores. One option for communicating with this robot is to use the MR/E, where human family members wear futuristic light weight MR glasses resembling sunglasses. Using this environment, the mother of the house can leave a do not enter thought crumb outside the door of her crafts-room to keep the robot out, or the father can mark areas of the garden that he would like the robot to weed. The robot also leaves thought crumbs for the humans, indicating things such as areas which were difficult to clean, or leaving an apology note beside a vase that the robot had broken during cleaning. Returning from school, the children wear the MR glasses and use a bubblegram menu on the robot to select which lunch they want packed for the following day. Later in the evening, while reading a book, the father verbally asks the robot to do an internet search regarding the book. Using bubblegrams, the robot displays the website to the father, allowing him to interact with it. This interface can be used as a portable computer, allowing human users to surf the internet, check their email, or watch a video.

A household robot also uses decorations around the house. These decorations represent various observations by the robot, such as favourite pictures or favourite places. They could also be used to illustrate places that a robot does not like, such as an area where it broke something, or the top of a stairwell where it had once fallen down (idea inspired by [11]).

6. PRELIMINARY PROTOTYPE
In order to test the various ideas and techniques presented in this paper, we are developing a preliminary prototype. This section presents the details, structure, and decisions surrounding the prototype.

In order to get a working prototype which uses the MR/E, there are a few problems which need to be solved. First, we need to select appropriate MR equipment for the humans to use and a set of robots with sufficient capability to participate in the MR/E. Second, a computer vision system needs to be implemented which can identify locations in the physical space for thought crumbs and decorations, and identify robots for the bubblegrams. Thirdly, an interaction system must be developed which allows human users to interact with the MR elements. Finally, a shared digital space, representing the digital interaction environment of the MR/E, must be created and implemented. With these steps implemented, we will be left with a prototype which can be used to evaluate the techniques presented here.

6.1 Equipment and MR Platform
When selecting the MR equipment for the human users to use, the main selection criteria are usability and comfort. This means that in addition to being able to render MR elements, the system must be portable and comfortable, allowing the user to move around an environment and to use the system for a reasonable length of time (up to about thirty minutes). In addition to this, the system must be able to access a local network to allow communication with the robots.

As discussed in section 3, head-mounted displays (HMDs) are well suited for this application. After surveying the many HMD models available, we selected the Jcuiti DV920 HMD. This model offers reasonable resolution (640 × 480 pixels) and is extremely light weight and portable, with the display weighing only 3.5oz. To obtain see-through capability, we attached a stripped-down and modified Creative Web-cam to the front centre of the goggles. A good comparison of video see-through vs optical see-through, and motivation for video see-through, is given in [4]. To power these modified glasses, a wearable computer must be used. We decided against connecting the user to a desktop via long cables for comfort and usability reasons. For the wearable computer, we are planning on buying an ultra-portable personal computer (UPC) such as the Sony VGN-U50 (550g, 167mm(W) × 108mm(L) × 26.4mm(H)), as this computer can be comfortably carried for extended periods of time and does not get overly hot. In the meantime, we are using a Toshiba tablet PC (carried in hand) to develop and evaluate the system.

For the robots, we are using Sony AIBO robot dogs. These dogs offer versatile capabilities in both the physical and digital aspects of the MR/E; they are mobile, have built-in vision systems, and have a fair amount of computational power. In addition to this, they have wireless networking capabilities, allowing them to connect to the human users.

6.2 Computer Vision
This preliminary prototype must be able to recognise landmarks for the thought crumbs and decorations, and to recognise Sony AIBOs for the bubblegrams. Recognition of landmarks is a different problem than recognition of AIBOs, given that the appearance of the AIBOs is known, but the vision must select unique landmarks out of an unmapped environment. Even with the AIBOs, vision is complicated by the diversity of the AIBO; it can sit, stand, fall on its side, move it’s head, and display a wide variety of LED configurations. To simplify this issue for the purposes of this prototype, constraints have been added to both the landmark detection and the AIBO detection. For the unique landmarks, a test environment will be setup where the landmarks are pre-selected and physically marked using unique markers. This way, the computer vision has only to recognise the specifically-designed markers and does not have to interpret the physical space. To simplify the AIBO finding, the AIBO is restricted to a particular set of poses; the AIBO will always be standing or walking in the same pose, and will always have its lights shut off.
While stronger vision algorithms may be needed before the
techniques presented in this paper can be fully realised, the
current implementation is sufficient for testing purposes.

With these constraints in place, we have managed to use
a single algorithm for both recognition problems. We have
used the Intel OpenCV[6] library to implement and employ
a technique developed by Viola and Jones, which offers rapid
and robust object-detection[19]. This object detection uses
computer learning methods to create classifiers for specific
objects. While this has not yet been implemented for the
unique location markers, this is currently implemented and
working well for the detection of AIBOs.

6.3 Interaction System
Many MRIE elements allow for direct interaction with MR
elements, and so a system must be implemented which al-

6.4 Shared Digital Space
As previously described, the MRIE consists of a shared digi-
tal space integrated into the shared physical space. In order
to realise this digital space, there must be a system which
entities in the space can use to convey the digital informa-
tion. Furthermore, this system should be always accessible
from within the space, as some MRIE elements are perma-
nent within the space.

The approach used in this prototype is to implement a cen-
tral server which all entities within the space connect to for
the digital interaction. Each entity can place MR entities
onto the server and can view the entities on the server in
relation to their location in the environment. This server
provides an interface which allows entities to specify MR
elements in terms of their mapping in our taxonomy, and
will also offer templates to represent bubblegrams, thought
crumbs, and decorations.

7. FUTURE WORK
This paper presented a preliminary prototype design which
could be used to implement the MRIE. The immediate fu-
ture work is to finish this prototype, and to utilise it for
evaluation of the MRIE and the techniques presented. To
evaluate the techniques, a comprehensive evaluation criteria
must be developed, combining quantitative and qualitative
aspects as a means to compare the effectiveness of particular

tions, and bubblegrams, and the mapping of these to the
taxonomy and the interaction field.

In order to evaluate the various MRIE techniques, this paper
also presented a design outline of a preliminary prototype.
Once this prototype is developed, an evaluation system will
be devised and the prototype can be used as a platform for
evaluating various MRIE techniques in practice.

8. CONCLUSION
Robot technology is advancing steadily, and it is important
that we understand the various issues and problems sur-
rounding interaction with robots. The fact that robots re-
side and interact in both the digital and physical worlds
introduces interesting interaction challenges. To meet these
challenges, we propose a solution called the MR Integrated
Environment (MRIE) which provides a virtual environment
of graphics and sound integrated directly into the real world.
This environment capitalises on robots being both digital
and physical entities, allowing a robot to use the entire
shared physical environment as their digital interaction space.
Using mixed reality, this environment allows a human user
to interact with a robot’s ideas and thoughts directly within
their shared physical interaction space.

We also offer a taxonomy of the MRIE as a method of or-
ganising and classifying the various interaction techniques
that this environment offers. As a method of conceptualis-
ing our taxonomy we present the notion of an interaction
field, a four-dimensional space representing the range of po-
tential MRIE interaction techniques. We demonstrate the
MRIE and taxonomy through the introduction and discus-
sion of three interaction techniques, thought crumbs, deco-
rations and bubblegrams, and the mapping of these to the
taxonomy and the interaction field.

9. REFERENCES

The MagicBook: Moving Seamlessly Between Reality


