



The European Coordination Hub for Open Robotics Development

CLARC project

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Servicio Andaluz de Salud
CONSEJERÍA DE SALUD

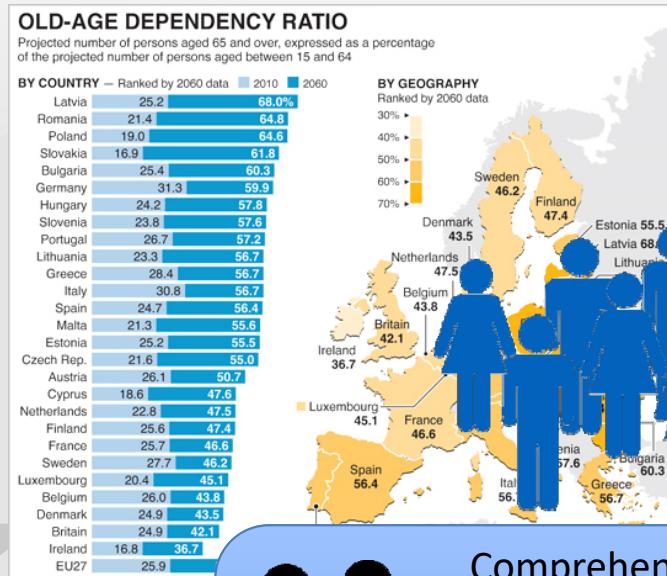


Universidad
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Background / motivation



The profile of aging is changing dramatically

loss of independence
 MUST NOT BE an
 inevitable consequence
 of aging

Comprehensive Geriatric Assessment (CGA)

- ✓ Individualized
- ✓ Periodic
- ✓ Patients and relatives



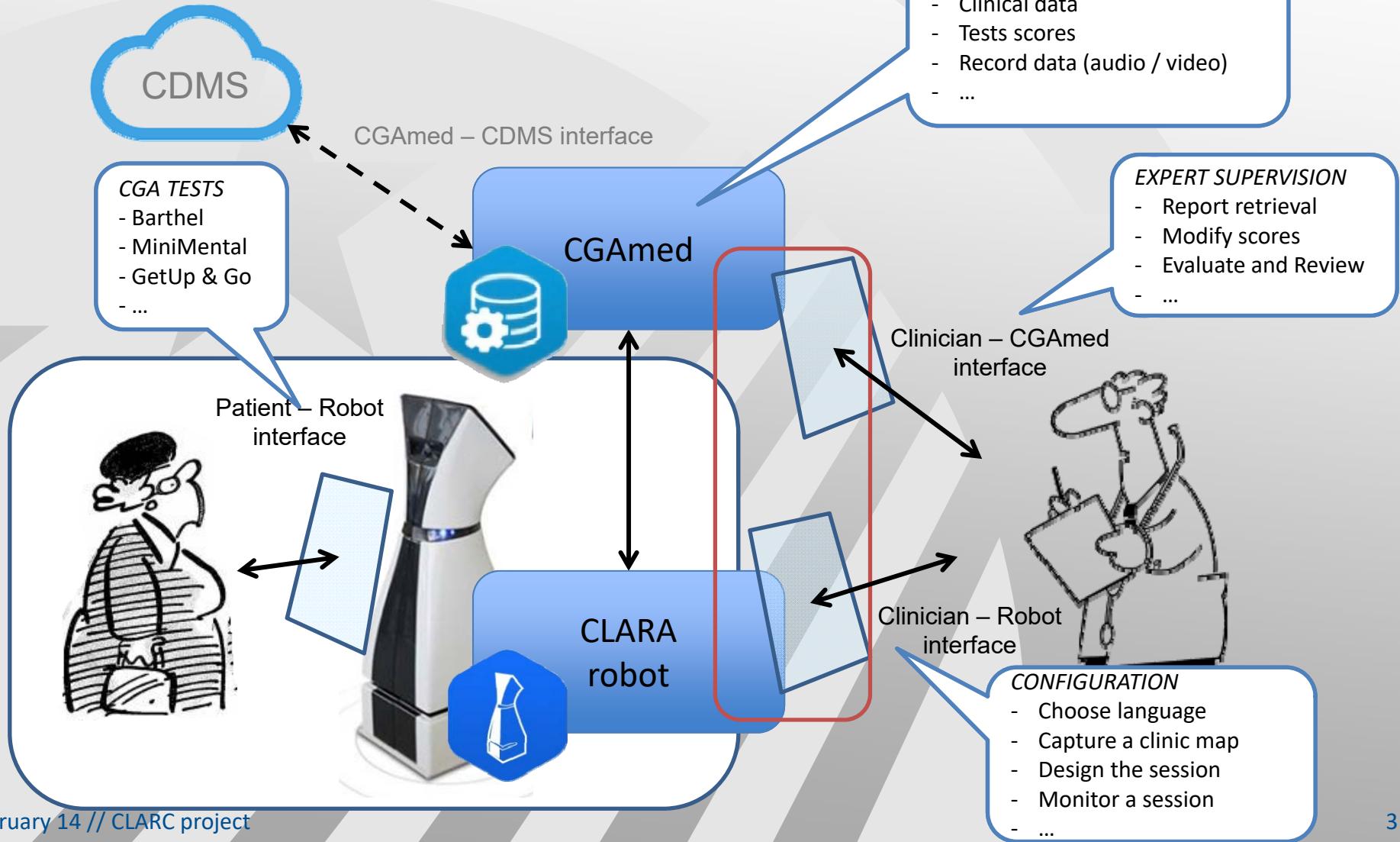
- ✓ Evidence-based interventions
- ✓ Individualized care plans



Healthcare services has problems for providing such as attention to an increasing population → why do not develop a tool for help them?

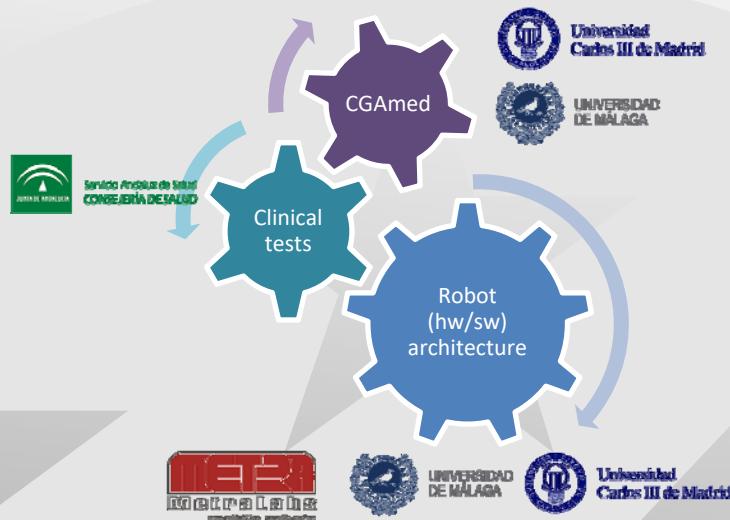
Technical progress

CLARC – Smart Clinic Assistant Robot for CGA

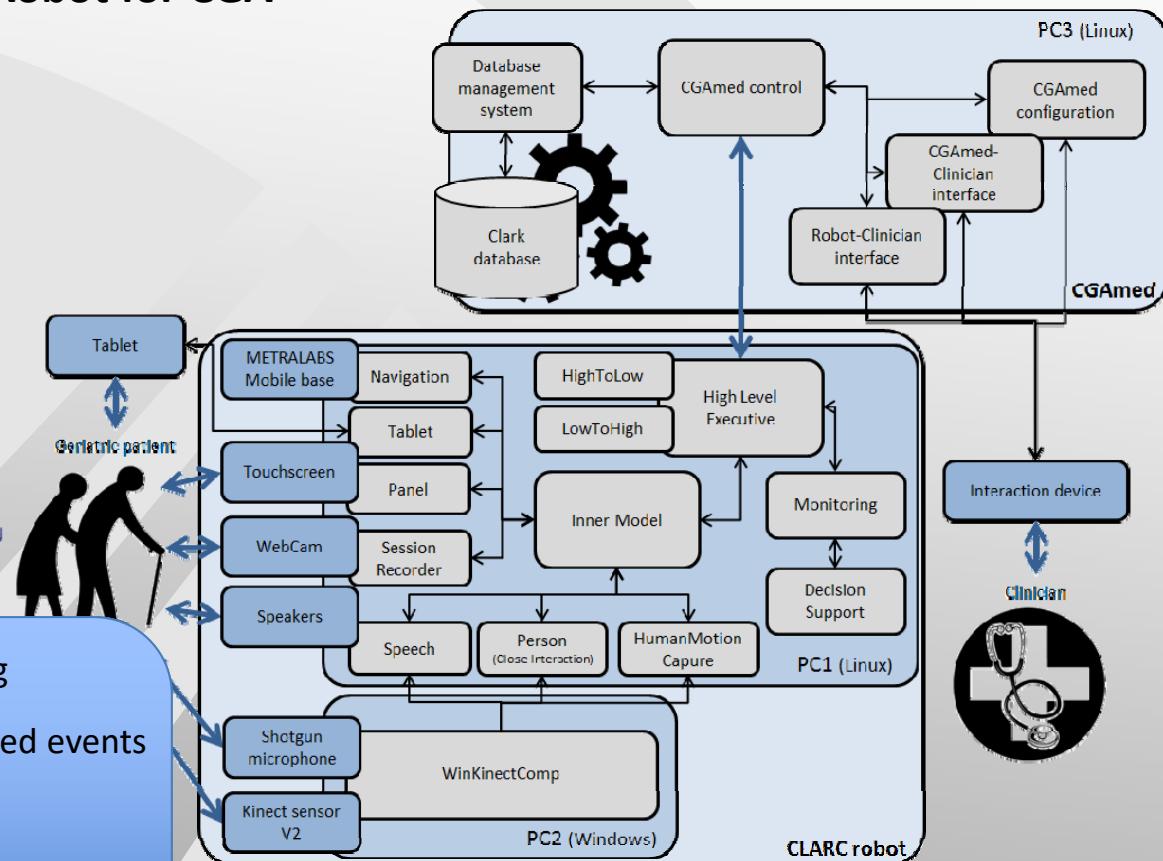


Technical progress

CLARC – Smart Clinic Assistant Robot for CGA



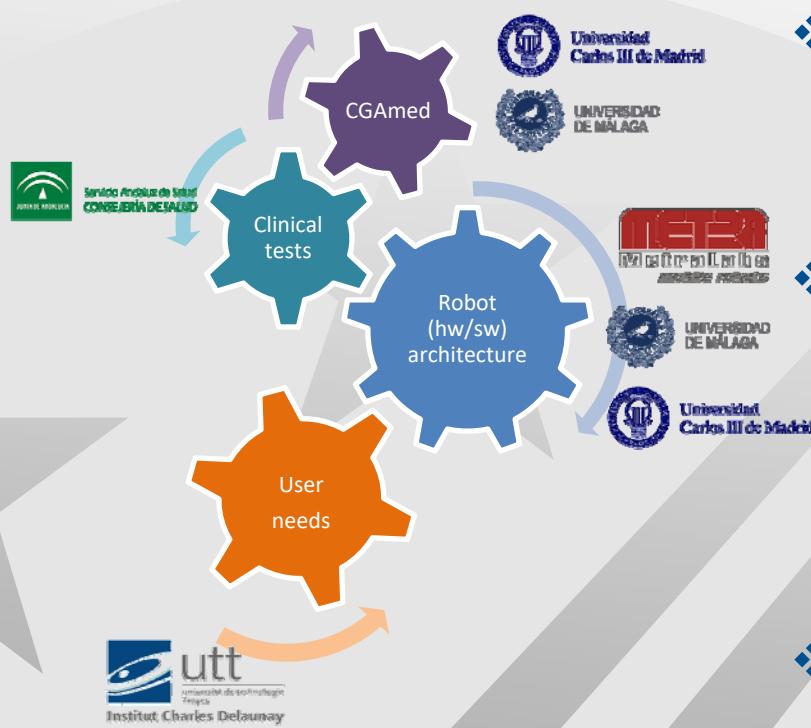
- ✓ Automatic monitoring and planning
- ✓ Autonomous response to unexpected events
- ✓ Mobility and autonomy
- ✓ Multi-language support
- ✓ Specialised interfaces
- ✓ Automatic scoring



End-user involvement?

- Acceptable by patients and relatives ??
- Usable by healthcare professionals ??

Technical progress



Participatory and user-centred Design Approach

❖ Users

- Seniors (potential patients)
- Health professionals

❖ Beginning of Phase 2: User requirements analysis

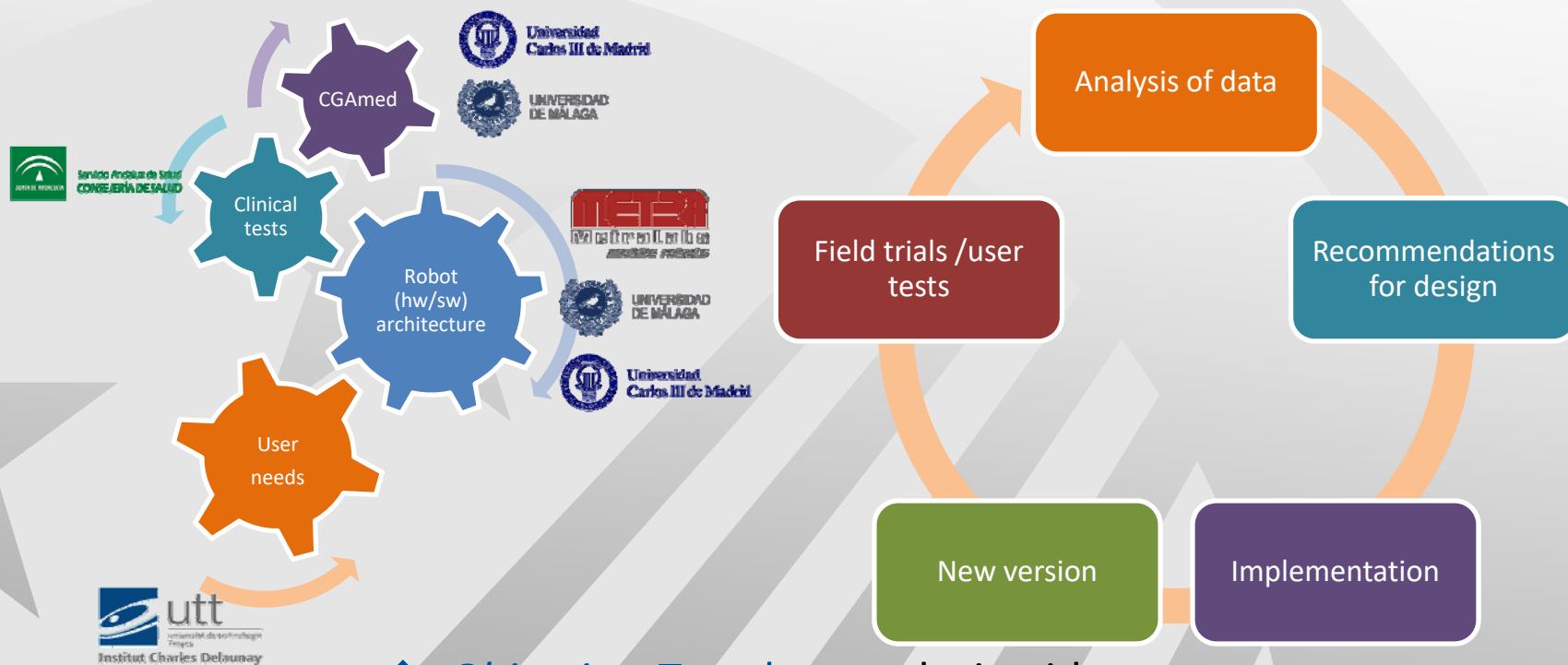
- User tests (based on working prototype)
- Participatory workshops
- Interviews

❖ January – Consortium meeting – Data

- 10 user tests – Barthel + Get Up & Go (French)
- 3 user tests – Minimental (English)
 - 13 post-test interviews
- 5 interviews of health professionals (geriatricians, physiotherapist, nurse, retirement home director)

Technical progress

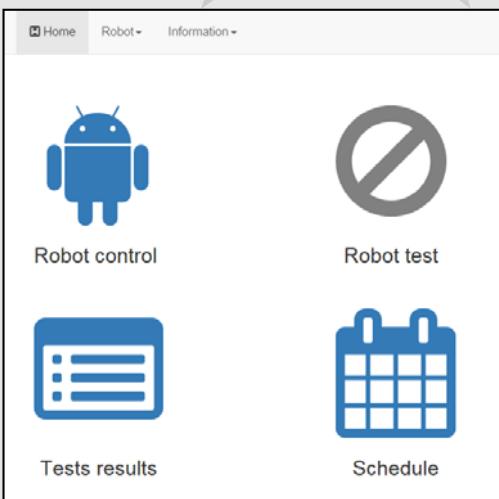
User analysis → Recommendations



❖ Objective: Translate to design ideas

- ✓ Users' needs
 - what patients value – interaction with doctor
 - health professionals' practices and habits
- ✓ Analysis of users' activity with the robot (difficulties in interacting)

Demonstrator/ prototype



- ❖ First results: hypothesis of use case confirmed
 - Acceptability of robot – seniors
 - ✓ feel at ease doing the test
 - ✓ easy interaction
 - Usefulness for health professionals
 - ✓ Geriatrician: greater efficiency in follow-up
 - ✓ Nurse: more time for relational

Impact from participation in ECHORD++



ABSTRACT Reasoning about phenomena from the outer world is intimately tied with the existence of an internal representation of this external reality. From a cognitive perspective, this implies the establishment of a connection between the two.

Abstract—Robots require a close coupling of perception and action. Cognitive robots go beyond this by requiring a further coupling between perception and action. From the perspective of robotics, this coupling needs to emphasize a tightly integrated perception-action system, which is loosely connected to some form of cognitive system such as a planner. At the other end, from the perspective of automated planning, the emphasis is on a highly functional system that, taken to its extremes, will perceptual and action modules as independent functions. This paper proposes to join both perspectives through a specific cognitive architecture where the responses of all modules on the software architecture (perception or actions) are grounded using the same set of symbols. This allows to generalize the signal-to-symbol divide that separates classical perceptormotor and automated planning systems, helping the resulting software architecture where all software modules interact using the same tokens.

Index Terms—cognitive robotics, inner representations, symbol grounding

I. INTRODUCTION

The world could mean more...
The world is intimately tied with the existence of an internal representation of this external reality. From a cognitive perspective, this implies the establish-

ment of a connection between the two.

Communication is the best mechanism to connect the components of the system [6].

Paradoxically, this was considered more of an advantage by Hartley [8], as

The use of the state of the world as the best mechanism to communicate software components was pointed out by Flynn and Brooks [6], as a way for reducing the large and close dependence of the components within the subsystem architecture.

Thank you.
