The Aspect Transition Graph: an Affordance-Based Model

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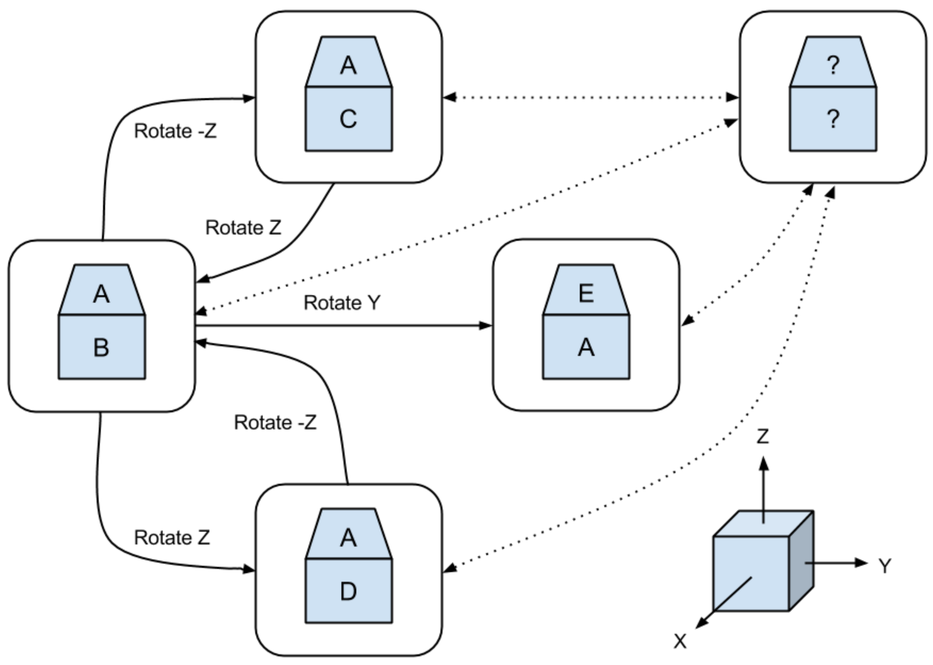
Abstract - Introduces an affordance-based model that is grounded in the robots own action and perception.

Affordance - The opportunities for action provided by a particular object or environment.

Aspect Transition Graph (ATG)

- Each object is modeled as an ATG.
- An ATG is a directed graph $G = (\mathcal{X},\mathcal{U})$, composed of a set of aspect nodes $\mathcal{X}$ connected by a set of action edges $\mathcal{U}$.
- Each aspect node $x \in \mathcal{X}$ represents the features of an object that are measurable given a set of sensors and their geometry relative to the object.



Learning Models

- An ATG is added to the robot memory $\mathcal{M}$ only if the presented object has not been presented to the robot in the past.
- Given a sequence of observations $z_{1:t}$ and actions $a_{1:t}$ during trial T, the probability that the presented object O_T during trial T is novel can be calculated;

$$
\begin{aligned}
& p(O_T \notin \mathcal{S}_{T-1} | z_{1:t}, a_{1:t}, \mathcal{M}) \\
&= \sum_{o_i \notin \mathcal{S}_{T-1}} p(O_T = o_i | z_{1:t}, a_{1:t}, \mathcal{M}) \\
&= \sum_{o_i \notin \mathcal{S}_{T-1}} \sum_{x_t \in \mathcal{X}_i} p(x_t | z_{1:t}, a_{1:t}).
\end{aligned}
$$

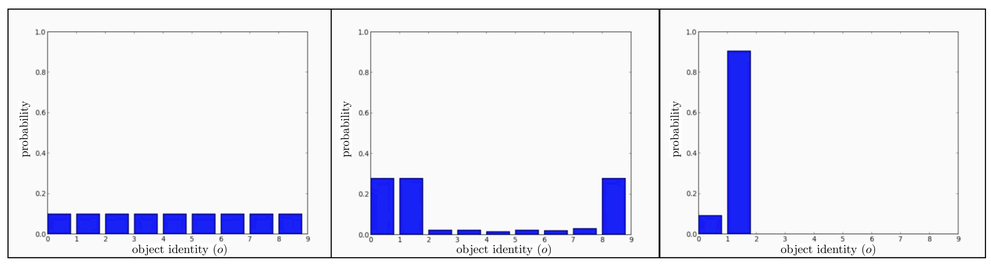
Notation	Definition
x_t	the aspect at time t
z_t	the measurement data at time t
a_t	the control data at time t
$\mathcal{M}$	the current robot memory
O_T	the object given to the robot at the Tth trial
o_j	the object labeled id j
$\mathcal{S}_T$	the set of objects given to the robot up to the Tth trial, $O_i \in \mathcal{S}_T \quad i = 1 \ldots T$

Action Selection Strategy

- The action a_t that minimizes the expected entropy over the random variable O_T representing the object identity is selected.

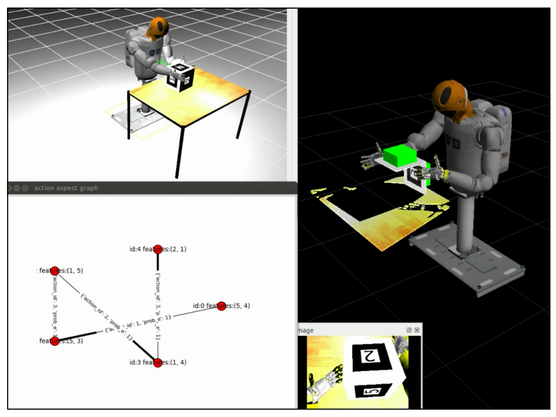
$$
\begin{aligned}
& \underset{a_t}{\text{argmin}}\ E(H(O_T | z_{t+1}, a_t, z_{1:t}, a_{1:t-1})) \\
&= \underset{a_t}{\text{argmin}} \sum_{z_{t+1}} H(O_T | z_{t+1}, a_t, z_{1:t}, a_{1:t-1}) \times \\
& p(z_{t+1} | a_t, z_{1:t}, a_{1:t-1}).
\end{aligned}
$$

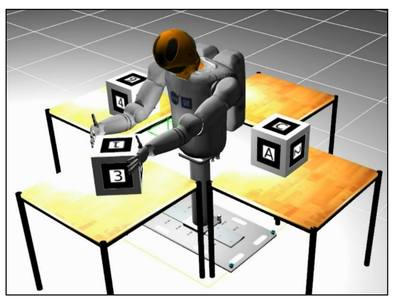
- Future observation is estimated through object models created from past observation.
- Once an object is recognized, the actions on the shortest path from the current aspect to the goal aspect is selected.



Experiments

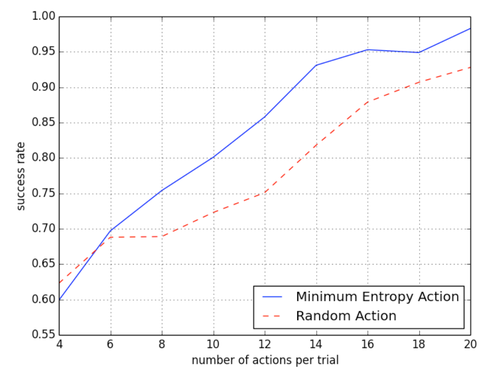
- The robot builds up a set of object models through interacting with random objects one at a time.
- Evaluated based on whether the robot can identify novel objects or recognize which object it corresponds to in memory.





Results

- Each test involves 100 trials and starts with an empty robot memory $\mathcal{M}$.
- The efficiency of the planner is tested against a random policy.
- Successfully reaches goal aspects in spelling task.



Test	Correct Identification	Correct Recognition	Success Rate
1	80/100	20/21	79%
2	79/100	25/27	77%
3	87/100	21/25	83%
4	78/100	26/28	76%
5	84/100	24/27	81%
average	81.6%	90.7%	79.2%

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