

TELEROBOTICS,

AUTOMATION,

TELEROBOTICS,

AND HUMAN

AUTOMATION,

SUPERVISORY

AND HUMAN

CONTROL

SUPERVISORY

CONTROL

THOMAS B. SHERIDAN

Telerobotics Automation And Human Supervisory Control

Michael J. Patzek



Telerobotics Automation And Human Supervisory Control:

Telerobotics, Automation, and Human Supervisory Control Thomas B. Sheridan, 1992 For the past three decades the author and his colleagues in the MIT Man Machine Systems Laboratory have been carrying out experimental research in the area of teleoperation telerobotics and supervisory control a new form of technology that allows humans to work through machines in hazardous environments and control complex systems such as aircraft and nuclear power plants This timely reference brings together a variety of theories and technologies that have emerged in a number of fields of application describing common themes presenting experiments and hardware embodiments as examples and discussing the advantages and the drawbacks of this new form of human machine interaction There are many places such as outer space the oceans and nuclear biologically and chemically toxic environments that are inaccessible or hazardous to humans but in which work needs to be done Telerobotics remote supervision by human operators of robotic or semi automatic devices is a way to enter these difficult environments Yet it raises a host of problems such as the retrieval of sensory information for the human operator and how to control the remote devices with sufficient dexterity In its complete coverage of the theoretical and technological aspects of telerobotics and human computer cooperation in the control of complex systems this book moves beyond the simplistic notion of humans versus automation to provide the necessary background for exploring a new and informed cooperative relationship between humans and machines

Telepresence: Actual and Virtual Thomas B.

Sheridan, 2022-11-15 Telepresence Actual and Virtual explores the history of telepresence from the 1948 developments of master slave manipulation through to current telepresence technology used in space undersea surgery and telemedicine operations in nuclear and other hazardous environments policing and surveillance agriculture construction mining warehousing education amusement social media and other contexts It also describes the various operator hand and body controls and the corresponding telerobotic actuation of robotic hands arms and locomotion This book reviews the sensing and control technology its history and likely future and discusses the many research and policy issues that are raised The book also takes up key questions relating to social and ethical issues given that a person's mechanical reach is becoming unlimited enabling one to perform mischievous or harmful acts without identification and what that portends for future developments in telepresence including regulation and recommended directions of development The primary audience for this book is professionals interested in human robot interaction human factors engineering virtual reality applications to space and undersea exploration telemedicine and telesurgery firefighting mechanized agriculture policing drone surveillance warehouse parts fetching mining and military operations

Human-Computer Interaction Andrew Sears, Julie A.

Jacko, 2009-03-02 Hailed on first publication as a compendium of foundational principles and cutting edge research The Human Computer Interaction Handbook has become the gold standard reference in this field While human computer interaction may have emerged from within computing significant contributions have come from a variety of fields including

industrial engineering psychology education and graphic design No where is this more apparent then when designing solutions for users as diverse as children older adults and individuals with physical cognitive visual or hearing impairments Derived from select chapters in The Human Computer Interaction Handbook this volume emphasizes design for these groups and also discusses HCI in the context of specific domains including healthcare games and the aerospace industry *Design of Work and Development of Personnel in Advanced Manufacturing* Gavriel Salvendy, Waldemar Karwowski, 1994-03-31 Presents a framework of worldwide problems issues and solutions relevant to the design of work and development of personnel in advanced manufacturing systems Focuses on people and their central roles in automated production resulting from rapid computer based integration Addresses social technical organizational managerial and ecological design issues relating to manufacturing success and the business objectives of a firm Provides solutions to problems of integrating the human element into the production process *Analysis, Design and Evaluation of Man-Machine Systems* 1992 H.G. Stassen, 2014-06-28 Containing 4 plenary papers and 38 technical papers this volume contributes to the literature on the important subject of man machine systems The many topics discussed include human performance skills knowledge engineering and expert systems training procedures human performance and mental load models and human machine interfaces **Human-machine Interface for an Experimental System to Investigate Model-based Supervisory Control in Telerobotics** Theodore Thomas Blackmon, 1995 [Evaluation of Gaming Environments for Mixed Reality Interfaces and Human Supervisory Control in Telerobotics](#) Ida Bagus Kerthyayana Manuaba, 2014 Telerobotics refers to a branch of technology that deals with controlling a robot from a distance It is commonly used to access difficult environments reduce operating costs and to improve comfort and safety However difficulties have emerged in telerobotics development Effective telerobotics requires maximising operator performance and previous research has identified issues which reduce operator performance such as operator attention being divided across the numerous custom built interfaces and continuous operator involvement in a high workload situation potentially causing exhaustion and subsequent operator error This thesis evaluates mixed reality and human supervisory control concepts in a gaming engine environment for telerobotics This concept is proposed in order to improve the effectiveness of current technology in telerobotic interfaces Four experiments are reported in this thesis which covers virtual gaming environments mixed reality interfaces and human supervisory control and aims to advance telerobotics technology This thesis argues that gaming environments are useful for building telerobotic interfaces and examines the properties required for telerobotics A useful feature provided by gaming environments is that of overlying video on virtual objects to support mixed reality interfaces Experiments in this thesis show that mixed reality interfaces provide useful information without distracting the operator from the task This thesis introduces two response models based on the planning process of human supervisory control Adaptation and Queue response models The experimental results show superior user performance under these two response models compared to direct manual control In

the final experiment a large number of novice users with a diversity of backgrounds used a robot arm to push blocks into a hole by using these two response models Further analyses on evaluating the user performance on the interfaces with two response models were found to be well fitted by a Weibull distribution Operators preferred the interface with the Queue response model over the interface with the Adaptation response model and human supervisory control over direct manual control It is expected that the increased sophistication of control commands in a production system will usually be greater than those that were tested in this thesis where limited time was available for automation development Where that is the case the increases in human productivity using human supervisory control found in this experiment can be expected to be greater The research conducted here has shown that mixed reality in gaming environments when combined with human supervisory control offers a good route for overcoming limitations in current telerobotics technology Practical applications would benefit by the application of these methods making it possible for the operator to have the necessary information available in a convenient and non distracting form considerably improving productivity

Point-and-direct Telerobotics
David John Cannon,1992 The Effect of Automation Level and Fidelity on the Human Supervisory Control of Multiple Remotely Operated Vehicles Heath Anthony Ruff,2000 Advances in Telerobotics Manuel Ferre,Martin Buss,Rafael Aracil,Claudio Melchiorri,Carlos Balaguer,2007-08-10 A fascinating book that covers in detail all of the most recent advances in Telerobotics A must read for scientists researchers and students in teleoperation it describes everything from methods and experimental results to applications and developments Its three sections cover human system interfaces control and applications

Advanced Guidance and Control Aspects in Robotics ,1994 To ensure the capability of defense a demand for equipment and systems which can be embraced under the title of Robotics will emerge in the near future In this context Robotics represents a specific problem area involving all the guidance and control functions which are associated with achieving goal oriented autonomous behavior in structured and unstructured environments for mobile and manipulator systems as applied to ground sea air and space operations Related robotic systems must combine constituent functions such as intelligent decision making control manipulation motion sensing and communication The scope of the special course will cover new developments in the areas of autonomous navigation for planetary and surface systems and control and operations of remote manipulators

Transitioning to Autonomy Ronald McLeod,2026-02-11 Whenever automation is introduced to control real time activities or processes the role of the human changes from being a manual controller to being a supervisory controller Whether the activity is the control of vehicles industrial processes or is in defence healthcare or elsewhere the work performed by the people who are expected to monitor and supervise the automation places new demands on their attention perception and cognition Those demands can be significant and challenging and this book aims to address that

Transitioning to Autonomy The Psychology of Human Supervisory Control focuses on the transition period when automation is being introduced and the human needs to learn and develop the competence to perform their new role effectively The first

Part extracts general lessons from the author's experience taking ownership of a new car which under certain circumstances was capable of driving autonomously Part 2 explores the psychology behind the lessons extracted in Part 1 and proposes a comprehensive model of human supervisory control The final Part focuses on six principal risks associated with human supervisory control and examines how the expectation that people will be proactive in monitoring for threats to the automation's performance is often relied on as a defence or Barrier against serious adverse events The core benefit for the reader is a deeper understanding of what it takes cognitively emotionally and organisationally to ensure safe and effective human oversight in the age of automation It aims to give the reader the lowdown on delivering safer systems The book is for managers engineers safety professionals and those from other technical disciplines who have responsibility for the design development and or assurance of products that automate the control of real time activities it's for regulators and others responsible for setting policy and ensuring products automating real time activities are safe and it's for Human Factors and other professionals who need to understand and develop competence in aspects of the psychology associated with automated systems

Human-robot Interaction Michael A. Goodrich, Alan C. Schultz, 2007 Presents a unified treatment of HRI related issues identifies key themes and discusses challenge problems that are likely to shape the field in the near future The survey includes research results from a cross section of the universities government efforts industry labs and countries that contribute to HRI

The Effect of Automation Levels on Human Supervisory Awareness and Judgement of Simulated Robotic Activities Michael J. Patzek, 2004

Supervisory Control in Automated Manufacturing Processes T. Govindaraj, Georgia Institute of Technology. School of Industrial and Systems Engineering. Project no. E-24-635, 1992

Optimal Supervisory Control of Automated Manufacturing Systems Yufeng Chen, Zhiwu Li, 2013-01-23 This monograph presents the state of the art developments in the design of behaviorally and structurally optimal liveness enforcing Petri net supervisors with computationally tractable approaches It details optimal supervisory control problems arising in automated production systems and outlines a methodology to achieve the optimality purposes of deadlock prevention via converting a variety of problems under consideration into integer linear programming models The book includes a reference bibliography at the end of each chapter and a complete index

Supervisory Control And Data Acquisition System Ashish Upadhyay, Sachin Upadhyay, 2016-05-10

Human Robot Interaction Concepts for Human Supervisory Control Ans Telemaintenance Applications in an Industry 4.0 Environment Doris Aschenbrenner, 2017

Remote Control Robotics Craig Sayers, 2012-12-06 Increasingly robots are being used in environments inhospitable to humans such as the deep ocean inside nuclear reactors and in deep space Such robots are controlled by remote links to human operators who may be close by or thousands of miles away The techniques used to control these robots is the subject of this book The author begins with a basic introduction to robot control and then considers the important problems to be overcome delays or noisy control lines feedback and response information and predictive displays Readers are assumed to

have a basic understanding of robotics though this may be their first exposure to the subject of telerobotics Professional engineers and roboticists will find this an invaluable introduction to this subject HUMAN MACHINE COOPERATIVE TELEROBOTICS. William R. Hamel, Spivey Douglass, Ge Zhang, Sewoong Kim, Pamela Murray, Yang Shou, Sriram Sridharan, Scott Thayer, Rajiv V. Dubey, 2003 The remediation and deactivation and decommissioning D D of nuclear waste storage tanks using telerobotics is one of the most challenging tasks faced in environmental cleanup Since a number of tanks have reached the end of their design life and some of them have leaks the unstructured uncertain and radioactive environment makes the work inefficient and expensive However the execution time of teleoperation consumes ten to hundred times that of direct contact with an associated loss in quality Thus a considerable effort has been expended to improve the quality and efficiency of telerobotics by incorporating into teleoperation and robotic control functions such as planning trajectory generation vision and 3 D modeling One example is the Robot Task Space Analyzer RTSA which has been developed at the Robotics and Electromechanical Systems Laboratory REMSL at the University of Tennessee in support of the D D robotic work at the Oak Ridge National Laboratory and the National Energy Technology Laboratory This system builds 3 D models of the area of interest in task space through automatic image processing and or human interactive manual modeling The RTSA generates a task plan file which describes the execution of a task including manipulator and tooling motions The high level controller of the manipulator interprets the task plan file and executes the task automatically Thus if the environment is not highly unstructured a tooling task which interacts with environment will be executed in the autonomous mode Therefore the RTSA not only increases the system efficiency but also improves the system reliability because the operator will act as backstop for safe operation after the 3 D models and task plan files are generated However unstructured conditions of environment and tasks necessitate that the telerobot operates in the teleoperation mode for successful execution of task The inefficiency in the teleoperation mode led to the research described as Human Machine Cooperative Telerobotics HMCTR The HMCTR combines the telerobot with robotic control techniques to improve the system efficiency and reliability in teleoperation mode In this topical report the control strategy configuration and experimental results of Human Machines Cooperative Telerobotics HMCTR which modifies and limits the commands of human operator to follow the predefined constraints in the teleoperation mode is described The current implementation is a laboratory scale system that will be incorporated into an engineering scale system at the Oak Ridge National Laboratory in the future

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