

Towards Learning Processes in a Resilient Human-Robot System

Stéphane Zieba* Frédéric Vanderhaegen** *** ****
Philippe Polet*** **** ***** Toshiyuki Inagaki*

*Department of Risk Engineering, University of Tsukuba, Tsukuba, Japan (e-mail:zieba@css.risk.tsukuba.ac.jp,
inagaki@risk.tsukuba.ac.jp)

**Univ Lille Nord de France, F-59000 Lille, France

***UVHC, LAMIH, F-59313 Valenciennes, France

****CNRS, FRE3304, F-59313 Valenciennes, France (e-mail: philippe.polet@univ-valenciennes.fr,
frederic.vanderhaegen@univ-valenciennes.fr)

Abstract: This paper addresses the topic of learning in resilient systems, and more especially human-robot systems. Resilient systems aim at managing the occurrence of perturbations by taking into consideration their past experiences, either successes or failures. Capitalizing the management of perturbations is an essential part of a resilient process. Three ways of learning are discussed in this paper: learning from errors, learning from cooperation and learning from affordances.

Keywords: human-machine systems, resilience, learning systems, human-machine cooperation, affordances.
