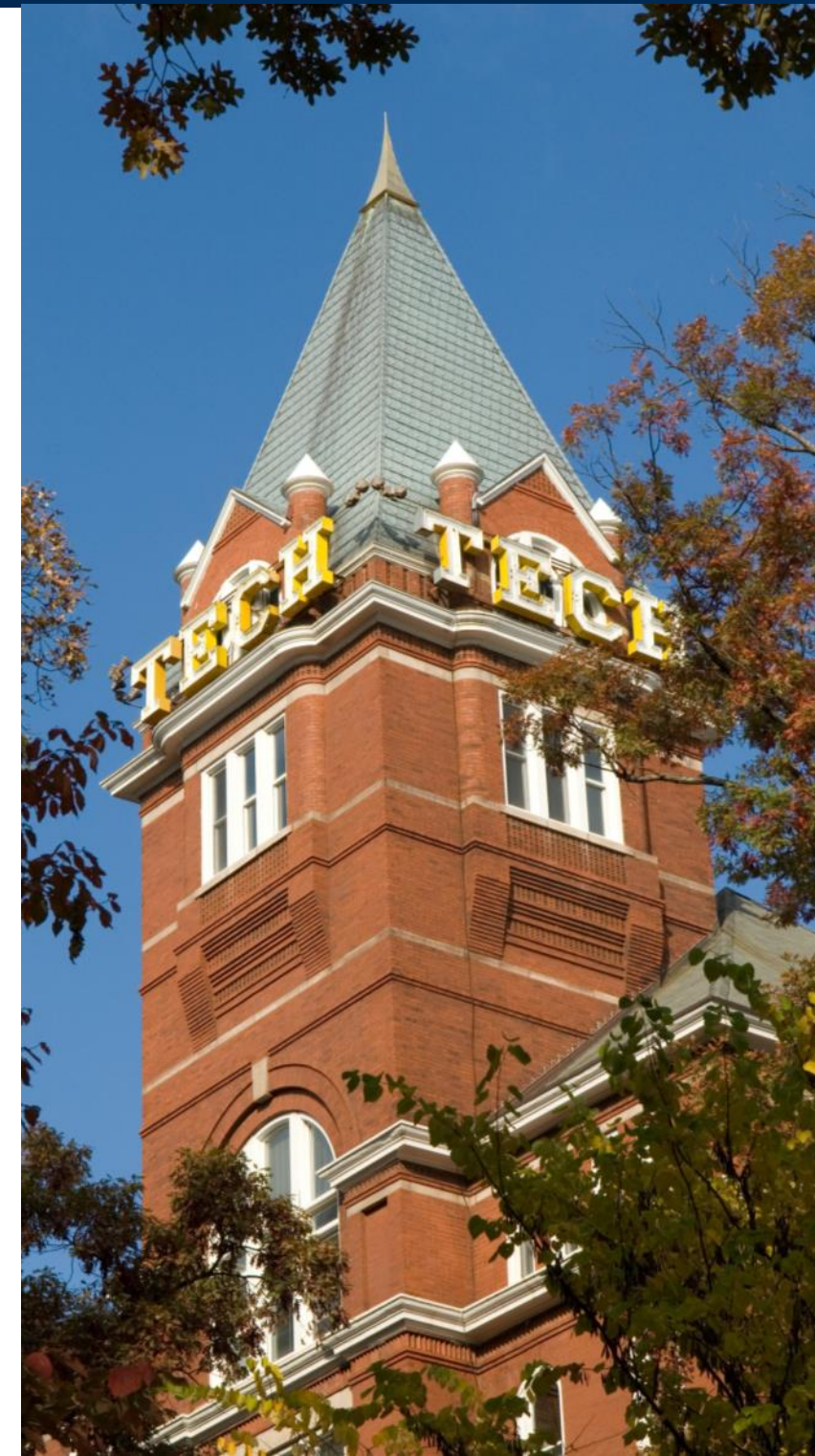


Robot Task Representation Working Group

Chair: Stephen Balakirsky (Stephen.Balakirsky@gtri.gatech.edu)

Co-Chair: Craig Schlenoff (Craig.Schlenoff@nist.gov)

Secretary: Signe Redfield (Signe@ieee.org)



How does your group define terminology (e.g., ontologies, glossaries, something else)?

- We are starting with general English language definitions, and will then formalize into an ontology
 - Our terminology is currently based off of the CORA standard
 - CORA is based off of Suggested Upper Merged Ontology (SUMO)
 - We are scheduled to have discussions at our meeting (tomorrow) on whether to keep this top order relationship

How do you define the following terms (as appropriate): robot, automated robot, teleoperated robot, environment, pose?

- In short, we don't
 - These are defined by CORA

How did you determine these definitions (e.g., adopted from other standards, consensus among group members, something else)?

- New definitions are determined by consensus
- Existing definitions are taken (wart and all) from other standards
 - Exceptions can be made when a term truly does not fit the spirit of our standard's effort
 - This has not yet happened

P1872-1 Adopted Terms

- A **task** is commanded to zero or more resources to achieve an intended outcome through zero or more actions
- A **command** is a task provided by another agent
- An **action** is an implementation of a command with the purpose of changing or maintaining the system state
- Further definitions required: Environment, System state, ...