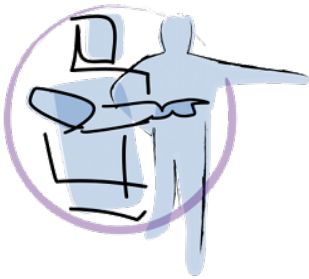


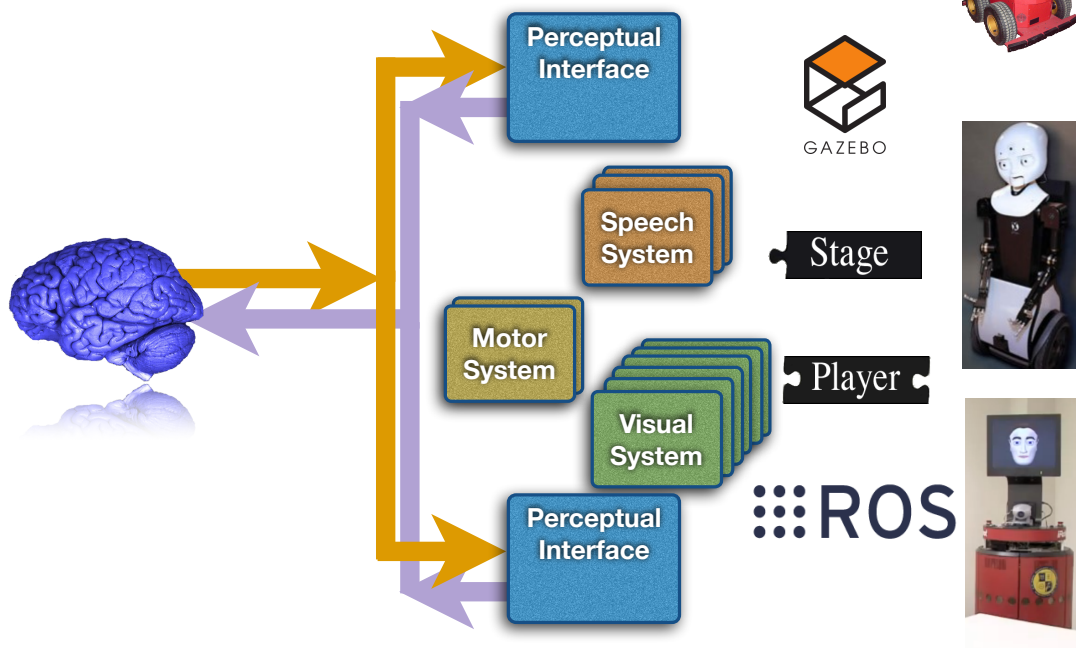
Interfacing for ~~Embodiment~~ *Robotics* *Scale*



Anthony M. Harrison
U.S. Naval Research Laboratory



~~Scalable~~ Interface *General*



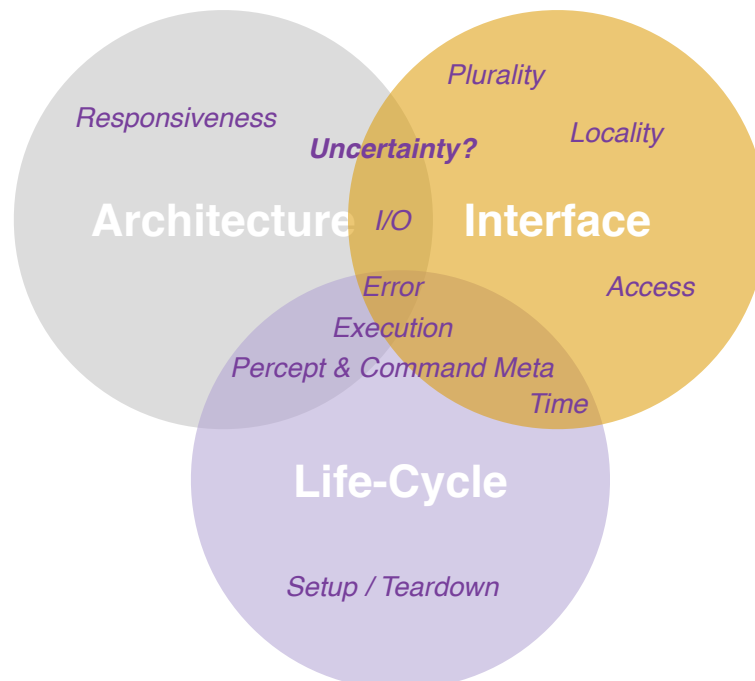


General Interface

- Network agnostic
 - Runtime configuration (protocol, transport, topology)
- Variable time & synchronization support
- Architecturally agnostic
 - Just percepts & actuators
- Multiple, composable interfaces
- Supports many different *interface use-cases*



Interface Use-Case





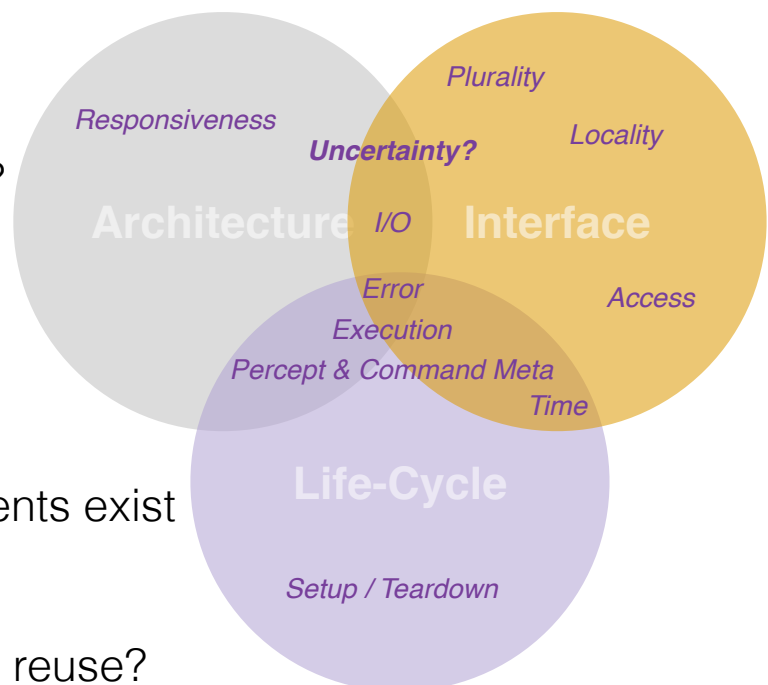
Mismatching Use-Cases?

- This session comes up every other workshop
 - One or two specific use-cases and custom solutions
 - Recommendation for a general solution that works well for a limited set of use-cases.
- Evolution of research & technology?
- One-off *use-cases*?
- Mismatch of *integration use-cases*?



Questions for Panel

- What are the different use-cases you've encountered?
- Can you accommodate other use-cases?
- What common elements exist across interfaces?
- What are you able to reuse?





Thank you!

