

## **Lazewatsky and Smart: A Panorama Interface for Telepresence Robots**

The authors choose a narrow field of view camera on a motorized head. Why do they suggest this is the right way to go from an HRI point of view? Can you think of an alternative method to accomplish the same HRI goals they mention in this regard? Compare your method, their method.

There is an interesting HRI problem here- there are two levels of saccading, or panning. One level is what the robot does for you. The second level is what the user, the controller, does on their computer screen, looking around a picture that may be showing on their large LCD computer display. Is this 2-step indirection a problem in your opinion? Regardless, design a solution that avoids this layering phenomenon.