Interactive cognitive user interface for robot teleoperation Bukeikhan Omarali UNIGE supervisor: Dr. Maurizio Valle QMUL supervisor: Dr. Ildar Farkhatdinov

## Goals

- Integrate visual, spatial and haptic feedback in a VR environment to improve the efficiency of remote robot control
- Feedback adaptation system which will automatically adjust the representation of the feedback to provide better awareness

## **Current State**

 Submitted a paper on hybrid control with interoperable teleoperation protocol to TAROS and extended abstract to UK Manipulation workshop



