Jointly Improving Parsing and Perception for Natural Language Commands through Human-Robot Dialog

Jesse Thomason∗, Aishwarya Padmakumar†, Jivko Sinapov‡, Nick Walker∗, Yuqian Jiang†, Harel Yedidsion†, Justin Hart†, Peter Stone†, and Raymond J. Mooney†

∗Paul G. Allen School of Computer Science and Engineering University of Washington
†Department of Computer Science University of Texas at Austin
‡Department of Computer Science Tufts University
jdtho@cs.washington.edu

Abstract—Natural language understanding in robots needs to be robust to a wide-range of both human speakers and human environments. Rather than force humans to use language that robots can understand, robots in human environments should dynamically adapt—continuously learning new language constructions and perceptual concepts as they are used in context. In this work, we present methods for parsing natural language to underlying meanings, and using robotic sensors to create multi-modal models of perceptual concepts. We combine these steps towards language understanding into a holistic agent for jointly improving parsing and perception on a robotic platform through human-robot dialog. We train and evaluate this agent on Amazon Mechanical Turk, then demonstrate it on a robotic platform initialized from conversational data gathered from Mechanical Turk. Our experiments show that improving both parsing and perception components from conversations improves communication quality and human ratings of the agent.

I. INTRODUCTION

Humans use natural language to articulate their thoughts and intentions to other people. As robots become ubiquitous across diverse human environments, such as homes, offices, factory floors, and hospitals, the need for smooth human-robot communication grows. The language we use to discuss these spaces varies, with domain-specific words and affordances in each (e.g., turn on the living room lights, move the pallet a few feet to the north, notify me if the patient’s condition changes). Pre-programming robots with fixed language understanding components limits them, since different speakers and environments use and elicit different words. Robots should leverage human speaking partners as a source of additional learning signals for language understanding. Rather than force humans to use language that robots around them can understand, robots should dynamically adapt—continually learning new language constructions and perceptual concepts as they are used in context. The main thrust of this paper is to bring together methods for improving semantic understanding and grounded perceptual understanding.

Untrained human users providing natural language commands to robots expect world knowledge, perceptual knowledge, and semantic understanding from verbal robots. Translating human utterances to semantic meanings helps handle the synonymy of commands and words (e.g., Bob for Robert), compositionality (e.g., Bob’s office, the light mug), and ambiguity (e.g., light in weight versus light in color). To learn a mapping between commands and their semantic forms, a semantic parser is often employed. Building a semantic parser requires expert annotation of a lexicon mapping words to their meanings, an ontology of relevant concepts in the world, and training examples of natural language sentences paired with composed meanings. In this work, we ameliorate this annotation effort by leveraging conversations that robots have with human users. We improve a parser built using sparse annotated resources using weak supervision from such conversations. This approach builds on past work, presented in full in [37].

To converse about the environment they share with humans, robots must gather and maintain world knowledge through perception. Some world knowledge can be modeled as static, such as the layout of a building, ownership relations between people and rooms (e.g., Bob’s office), or assignments between patients and doctors in a hospital. Other world knowledge is perceptual, such as whether an object is a mug, where some movable objects were last seen, and whether an object can be picked up and moved somewhere else. Gathering correspondences between objects in the world and perceptual concepts, or predicates, applicable to those objects (e.g., heavy, brown, mug) is a time-consuming annotation effort if performed exhaustively. In this work, we instead extract this information from natural human-robot conversations on-the-fly.

We present a holistic system for jointly improving parsing and perception on a robotic system for natural language commands through human-robot dialog. This learning agent uses clarification questions in a conversation with a human partner to understand language commands. The agent induces additional training data for a semantic parser, similar to prior
In this conversation, the agent has just asked a confirmation question—whether it has understood the right location from where the red can should be taken. The colored text here refers to the pink-outlined map below the conversation window.

work [37], strengthening its parsing over time. The agent also uses opportunistic active learning [39] to ask questions about nearby objects to refine multi-modal perceptual concept models [38] on-the-fly during command dialogs.

We evaluate this language understanding agent on Mechanical Turk with hundreds of users. Figure 1 shows the Mechanical Turk interface we created, with an example command and the beginning of a human-agent dialog. To demonstrate flexibility for understanding non-visual predicates, we also implement the agent on a physical robot with an arm [16], using the learning agent as a back-end to drive human-robot dialog.\footnote{The demonstration video can be viewed at https://youtu.be/PbOfteZ_CjC} As more training conversations are seen by the agent in Mechanical Turk, users are better able to communicate tasks to the agent. Users rate the agent more favorably for use in deployed tasks as more training conversations become available.

II. RELATED WORK

Instructing robots through natural language is essential for humans and robots to cooperate in shared environments. Research in this space spans semantic parsing, robotic perception and grounding, and human-robot dialog.

Semantic parsing has been used as a language understanding step in tasks involving unconstrained natural language instruction, where a robot must navigate an unseen environment using language guidance [19, 24, 25]. Recent methods perform semantic parsing translations using sequence to sequence [18, 14, 20] or sequence-to-tree [8] neural networks. One framework, based on generalized grounding graphs, aims to both understand human language requests about objects in the world and generate language requests regarding the shared environment [36]. Extensions of this framework can be used to memorize new semantic referents in a dialog, like this is my snack [30], or to reason about abstract sets and ordinality [29]. In this work, our agent can learn new referring expressions and novel perceptual concepts on-the-fly through dialog.

Mapping from a referring expression such as the red cup to an object referent in the world is an example of the symbol grounding problem [12]. Grounded language learning bridges internal representations of information in a machine with natural language. Most work in this space has grounded language using visual perception [10, 21, 42, 23]. There has been some work on combining language with sensory modalities other than vision, such as audio [17] and haptic [4, 11] signals. A recent survey attempts to cover this broad space of multi-modal representations of objects and concepts in machine learning [1]. Some neural methods bypass any explicit modeling of language predicates and instead train end-to-end on tasks such as localizing an object in a given image given a target query in natural language [13], and translating human instructions directly to grounded behavior like route-following [26] or question answering [7]. In this work, we explicitly model language predicates that refer to spatial relations and categories in an office environment, as well as perceptual predicates that refer to properties of objects, the latter of which is an open set.

Some researchers gather data for this kind of perceptual grounding using interaction with a human interlocutor. This combination of dialog and perception affords new opportunities, such as the robot asking questions targeting weaknesses in its understanding [38]. Previous work on learning to ground object attributes and names using dialog framed the data gathering phase as a 20 Questions-style [40] or I Spy [28, 38] game. Neural approaches have been used to train grounded robot-robot conversational agents [6], and may be applicable for human-robot dialog in future works. We do not use neural methods, which share a data hungry weakness and fail to converge to useful solutions when training examples are sparse, such as in human-robot dialogs where gathering environment-specific interactions is costly.

We present a robotic agent that understands requests for actions in natural language that include both domain knowledge (for example, a building floorplan) and environmental perceptual information (for example, learned properties of objects), using semantic parsing as an understanding step and learning multi-modal perceptual concept models using supervision elicited during conversations.

III. CONVERSATIONAL AGENT

We implement and evaluate a conversational dialog agent that uses a semantic parser to translate human utterances into semantic meaning representations, then grounds those meaning representations using both a static knowledge base of facts about an office environment and perceptual concept models.
that consider multi-modal representations of physical objects.\textsuperscript{2}

A. Semantic Parser

We use the Combinatory Categorial Grammar (CCG) formalism [35] in our lexicon to perform Cocke-Kasami-Younger (CKY) chart parsing [41] on input sentences, and use a unification-based grammar to add new lexical entries during training. We add ontological entries dynamically during conversations with human users (for example, when a new perceptual concept like red is used for the first time). In the interest of space, we refer the reader to other work in learning statistical parsers for details [22].

In order to assign a semantic meaning to a sequence of tokens, each token that is not skipped must have an entry in the lexicon from which its semantic meaning can be determined. We use word embeddings [27] to augment the lexicon at test time to attempt to recover from out-of-vocabulary words, an idea similar in spirit to previous work [2], but formally integrated into our parsing pipeline. This allows, for example, unseen word grab to use the lexical entry for the nearby (in embedding space), known word take at test time.

B. Multi-modal Perception

Once a command has been translated into a semantic form, grounding that semantic form to actions, objects, and rooms in the real world must take place before the robot can act on the command. For objects, perceptual concepts like red and heavy require considering sensory perception of physical objects. We build multi-modal concept models to connect robot perception to concept labels. We use multi-modal feature representations across various sensorimotor contexts by exploring those objects with a robot arm (Figures 2 and 3), as detailed in previous work [34, 38].

We connect these feature representations of objects to language labels by learning discriminative classifiers on the feature spaces for each perceptual language concept, as detailed in previous work [33, 38]. Relevant for this work, each trained classifier produces both a decision and a confidence (in $[0, 1]$) when evaluating a test object for a language concept (e.g., an object is red with confidence 0.8). These confidence values are also used to drive an opportunistic active learning strategy for improving concept models during conversations.

\textsuperscript{2}The source code for this conversational dialog agent, as well as the experiments described in the following section, can be found at https://github.com/thomason-jesse/grounded_dialog_agent

C. Language Grounding

To execute a command, an utterance is first translated into a semantic form. Some forms must be instantiated in a particular context. For example, the office by the kitchen refers to a physical location in an environment, but the utterance means different such locations depending on where it is uttered, and must be grounded to the current environment.

Static facts such as room types (office) and relations (owns(robert, room1)) can be looked up in a provided floor-plan, such that unambiguous noun phrases can be grounded with full confidence. For perceptual predicates, concept models return both a decision and a confidence value in $[0, 1]$.

Since there are multiple possible groundings for ambiguous utterances like the office and varied confidences for perceptual concept models on different objects, we create a confidence distribution over the possible groundings for a semantic parse. This confidence probability distribution is used as part of an update procedure for helping the agent understand the user’s intent during dialog.

D. Dialog Policy

We implement a conversational dialog agent $A$ for command understanding similar to that in previous work [37]. The differences between this agent and the previous one are: 1) grounding semantic parses in both static knowledge and perceptual knowledge; 2) dynamically adding new ontological predicates for novel perceptual concepts; 3) leveraging opportunistic active learning for refining perceptual concept models on-the-fly; and 4) semantic parser training from pairs of utterances and denotations.

a) Clarification Dialog Policy: Dialog begins with a human user commanding the robot to perform a task. The agent maintains a belief state modeling the unobserved true task in the user’s mind, and uses the language signals from the user to infer it. The command is first parsed by the agent’s semantic parser, then grounded against static and perceptual knowledge with denotation procedure, which results in a set of pairs of denotations of the semantic parser’s understanding of the command and associated confidence values. Using these
denotations and their confidence distribution, we update the agent’s belief state, then engage in a clarification dialog to refine that belief.

The agent’s belief state, $B$, is a mapping from semantic roles (components of the task) to probability distributions over the ontological constants that can fill those roles (action, patient, recipient, source, and goal).

The belief state for the action role is initialized with uniform probabilities across three actions (walk, deliver, and relocate). The remaining role belief states are initialized with half of the probability mass on an unknown constant, $\varnothing$, indicating that the role is not known or is not necessary for the action the user has in mind, and the remaining half of the probability mass is distributed uniformly across all constants that can fill the role.

We call the collection of beliefs from a single utterance, $x$ (a command or question answer), $B_x$, a mapping from semantic roles to the distribution over constants that can fill them. We update the agent’s belief based on new utterance $x$:

$$B(r, a) \leftarrow (1 - \rho)B(r, a) + \rho B_x(r, a),$$

(1)

for every semantic role $r$ and every constant $a$ (for example, as in Figure 4). The parameter $\rho$ controls how much to trust the new information versus the current belief (in our experiments, we set $\rho = 0.5$).

The dialog agent poses questions to the user regarding different semantic roles. The highest-probability constant for every semantic role in the current belief state $B$, together with which among those roles has the least probability, are used to select a question. Table I gives some examples of the policy $\pi$.

For confirmation questions, the confirmed $B_x$ constant(s) receive the whole probability mass for their roles, and $\rho$ is set to 1 for the update in Equation 1, such that $B$ reflects the confirmation. If a user denies a confirmation question, $B_x$ is constructed with the constants in the denied question given zero probability weight for their roles, and other constants given a uniform weight, such that the update in Equation 1 reduces the belief only for denied constants. A conversation concludes when the user has confirmed every semantic role.

b) Detecting Perceptual Words and Synonyms: When describing objects in the real world, humans can use words the agent has never heard before. Some of these are perceptual concepts—words that need to be grounded in the physical world. In prior work, a stopword list is used to remove non-content words, and all content words in human descriptions of objects are considered perceptual concept words [38, 39].

In this work, if one of the neighboring (among the nearest 3) words of unknown word $x_i$ (in word-embedding distance) has a semantic form involving a perceptual predicate, we ask the user whether the unseen word $x_i$ is also perceptual in nature. The question posed is: I haven’t heard the word ‘$x_i$’ before. Does it refer to properties of things, like a color, shape, or weight? If the user answers yes, we attempt to discover whether $x_i$ is a synonym of an already known perceptual concept, such as one of the identified neighbors.

We rank the nearest neighbors of $x_i$ by distance and sequentially ask the user whether the next nearest neighbor $t_p$ is a synonym of $x_i$. If so, new lexical entries are created to allow $x_i$ to function like $t_p$, including sharing an underlying perceptual concept model. For example, in our experiments, previously unseen word tall was added as a synonym for the known word long. If no synonym is identified, a new ontological concept is created to represent $x_i$. For example, in our experiments, the color concept word red was added with a new ontological predicate to represent it.

c) Opportunistic Active Learning during Conversation: We introduce opportunistic active learning questions as a sub-dialog routine for the agent, in which it can query about objects local to the human and the robot (e.g. objects in the room where the conversation is happening) to refine its perceptual concept models before applying them to the remote test object items (e.g. items that are physically in a different room but being discussed in the conversation), a strategy employed for object selection from language descriptions in previous work [39].

Objects in the nearby active training set can be labeled by asking the human questions during a conversation about whether particular predicates apply to them. Prior work established that an agent asking questions about both on-topic (used in the current conversation) and off-topic (irrelevant to the current user’s needs) predicates outperformed an agent that only asked about predicates in the current human description [39]. We allow our agent to ask both on- and off-topic questions, moving to off-topic ones only if there are no more useful on-topic labels to query. Our question selection strategy is similar to that described in this prior work [39]. Using this sub-dialog, the agent is able to query the user for labels on the active training objects, $O_{tr}$, to improve its perceptual classifiers before continuing its clarification conversation and possibly selecting a described object in the active test set, $O_{te}$.

E. Learning From Conversations

Past work retrained a semantic parser from conversations an agent has with a human [37]. In this work, we expand on this retraining procedure and make a distinction between denotation parses and latent semantic parses. That is, we differentiate between robert’s office and its denotation, $r_1$, where in the strategy presented in previous work, the denotation would be treated as the latent form of robert’s office, weakening its ability to generalize from induced data and creating more reliance on a robust initial lexicon. We first induce utterance-denotation pairs from conversations, then induce latent semantic forms that connect those utterances and denotations.

For details on inducing utterance-denotation pairs from conversations, we refer to previous work [37]. In this work, given an utterance-denotation pair, we discover a semantic parse that can be derived from the input utterance and has a denotation matching the known one for that utterance. We formulate this training and finding of the latent semantic form similar to past work on learning statistical, compositional
What should I do? Clarification
What should I deliver to
You want me to move
Fig. 4: Example belief update for the recipient role. This could arise from the question To whom should I bring something? being answered alice.

<table>
<thead>
<tr>
<th>Role</th>
<th>Question</th>
<th>Type</th>
</tr>
</thead>
<tbody>
<tr>
<td>action, patient, recipient, source, goal</td>
<td>What should I do?</td>
<td>Clarification</td>
</tr>
<tr>
<td>walk, source,</td>
<td>You want me to go somewhere?</td>
<td>Confirmation</td>
</tr>
<tr>
<td>deliver, goal,</td>
<td>What should I deliver to</td>
<td>Confirmation</td>
</tr>
<tr>
<td>relocate,</td>
<td>Where should I move something from on its way somewhere else?</td>
<td>Confirmation</td>
</tr>
<tr>
<td>relocate, source, goal,</td>
<td>You want me to move</td>
<td>Confirmation</td>
</tr>
<tr>
<td>relocate, source, goal,</td>
<td>-</td>
<td></td>
</tr>
</tbody>
</table>

TABLE I: Samples of the agent’s static dialog policy $\pi$ for mapping belief states (left) to questions (right). In the Mechanical Turk experiments described in Section IV, constants like people ($p_1$), objects ($o_1$), and rooms ($r_1, r_2$) were represented pictorially, with pronouns (this person, this, here, there) in place of their variables in the sentence shown.

IV. EXPERIMENTS

We evaluate our agent with hundreds of users through the Mechanical Turk interface, asking human users who instruct it to perform three tasks: navigation (Go to the lounge by the kitchen), delivery (Bring a red can to Bob), and relocation (Move an empty jar from the lounge by the kitchen to Alice’s office). After training the agent using data from conversations it had with users on Mechanical Turk, we instantiate the trained agent on a physical robot.

A. Experiment Design

We deploy the agent in a simulated office environment populated by rooms, people, and object items. We fix 8 of the 32 objects explored in prior work [34] as possible arguments to the tasks for our experiments (selected at random), and use the remaining 24 as training objects available for opportunistic active learning queries for learning concept models. We randomly split the set of possible tasks into initialization (10%), train (70%), and test sets (20%).

a) Initialization Phase: Sixteen users (graduate students at the university across several fields) engaged with a faux-agent using the web interface. They were shown one of each type of task, drawn from the initialization set, and gave two high-level commands for each (the faux-agent simply asked the user to rephrase each high-level command once, with not following clarification dialog). We used these commands as a scaffold on which to build an ontology, lexicon, and initial utterance-semantic parse pairs. Of them, 44 pairs, $D_0$, were used to train an initial parser.

b) Training Procedure: We use these initial parsing resources to create a baseline agent $A_1$ with a parser $P_1$ trained only on the initialization pairs $D_0$ mentioned above and concept models for several predicates $P_{c,1}$, but with no initial object examples against which to train them. All learning for the parser and perception modules arises naturally from conversations the agent has with humans.

We divide the training procedure into three phases, each associated with 8 objects from the active training set, which can be queried about during conversations by the agent. Between phases, the parser and perception models are retrained. Each phase $i$ is carried out by agent $A_i$, after which parser $P_{i+1}$ and concept predicates $P_{c,i+1}$ are trained to instantiate agent $A_{i+1}$.

After three training phases, agent $A_4$ with parser $P_4$ and perception models $P_{c,4}$ is tested by interacting with users trying to accomplish tasks from the unseen test set of tasks. We also test an ablation agent, $A_4^*$, with parser $P_4^*$ and perception models $P_{c,4}$ (trained perception with simply initialized parser).

c) Performance Metrics: Quantitatively, we measure the semantic f-score of each user on each task. This metric is a measure of the agreement between the task the user confirmed and the task they were instructed to convey, and is used as a measure of how close users came to conveying the correct task [5]. The metric is defined as the harmonic mean of the precision and recall between the sets $T_U$, the set of pairs of roles and constants the user confirmed, and $T_G$, the gold task specification pairs.

We also consider user’s answers to survey questions about whether they would use the agent for the three tasks in the real world (Figure 7). Each questions was answered on a 7-point Likert scale: Strongly Disagree (0), Disagree (1), Slightly Disagree (2), Neutral (3), Slightly Agree (4), Agree (5), Strongly Agree (6). Users are also able to provide optional, free-form text feedback as a part of completing this survey.

Semantic parsers [22]. At a high level, a beam of parses is created for the utterance, and these are grounded to discover which matches the target denotation (selecting among these parses the one with highest joint confidence between parsing and grounding). After inferring these latent parses, we train the parser on the discovered utterance-semantic parse pairs.
and their responses provide some anecdotal insight into their experiences with the agent.

B. Mechanical Turk Evaluation

Workers connect to our web interface and engage in three conversations, then fill out a survey about their experience using the agent. To avoid biasing workers towards certain words (linguistic priming), we present tasks by describing the target state of the world after the task is completed. For example, for the navigation task, the prompt is: *Give the robot a command to solve this problem: The robot should be at the X marked on the green map*, with a green-highlighted map visually marking the target. Figure 1 shows a clarification and confirmation question for the goal semantic role of the delivery task. The agent also asks questions in sub-dialogs regarding whether perceptual concept words apply to objects. Figure 5 shows an example of such a yes/no question and of the panel used for open-ended positive/negative example questions (asking, among available objects, which one a word does or does not apply to).

a) Human Intelligence Tasks (HITs): We run 50 HITs at a time on our server. For the train condition, we run two batches per fold of active training set objects, for a total of \(2 \times 3 \times 50 = 300\) workers. For the test conditions—without parser or perception training \((A_1)\), with perception training only \((A_4)\), and with parser and perception training \((A_4)\)—we run three batches of 50 workers each for a total of \(3 \times 50 = 150\) workers.

In addition to removing workers who timed out (2 hour limit) or had exceedingly long conversations (30 human dialog turns), we vet the remaining set of workers by removing repeat workers and workers who confirmed navigation commands with the agent for all three target tasks.

Table II gives a breakdown of the numbers of workers who engage with our HITs through different experimental conditions. Only workers who submit the HIT with the correct

3On inspection, these workers identify, during the navigation task (the first dialog), that the robot will advance to the next phase once a command is confirmed, and they continue issuing navigation commands because these are fast to resolve.

---

Fig. 5: Web interface for the agent asking whether a predicate applies to an object (Left), and for positive/negative examples (Right) (e.g., *could you show me one you would use the word ‘red’ when describing, or shake your head if there are none?*).

4For example, nine workers labeled a uniformly yellow mustard container as a positive example for red.
<table>
<thead>
<tr>
<th>Condition</th>
<th>Number of Workers</th>
<th>Submitted</th>
<th>Completed</th>
<th>Vetted</th>
<th>Nav. Correct</th>
<th>Del. Correct</th>
<th>Rel. Correct</th>
</tr>
</thead>
<tbody>
<tr>
<td>Train (A₁, A₂, A₃)</td>
<td>297</td>
<td>162</td>
<td>113</td>
<td>36</td>
<td>44</td>
<td>18</td>
<td></td>
</tr>
<tr>
<td>Untrained (A₁)</td>
<td>150</td>
<td>67</td>
<td>44</td>
<td>17</td>
<td>22</td>
<td>10</td>
<td></td>
</tr>
<tr>
<td>Test (A₄)</td>
<td>148</td>
<td>93</td>
<td>50</td>
<td>20</td>
<td>29</td>
<td>10</td>
<td></td>
</tr>
<tr>
<td>Test (A₄)</td>
<td>143</td>
<td>79</td>
<td>42</td>
<td>16</td>
<td>23</td>
<td>10</td>
<td></td>
</tr>
</tbody>
</table>

TABLE II: Breakdown of the number of workers in our experiment. We here count only workers that submitted the HIT with the correct code. Workers that completed all tasks and the survey finished the HIT entirely. Vetted workers’ data was kept for evaluation. The Train condition (A₁, A₂, A₃ agents) draws from the training set of tasks, while the Untrained (A₁ untrained agent), Test (A₄ agent with trained perception and untrained parser), and Test (A₄ agent with trained parser and perception) conditions draw from the test set of tasks.

![Graphs](image1.png)

Fig. 6: The average semantic slot \( f \) scores between the semantic roles in the target task and the task confirmed by the user.

![Survey Prompts](image2.png)

Fig. 7: Survey prompt responses about usability.

Fig. 8: The perceptual concept model learned for can after training from conversations with human users. The numbers below each object in the active test set represent their (rounded) portion of the distribution of probability based on outputs from the can concept model.

C. Physical Robot Implementation

For our embodied demonstration, we use the BWIBot [15, 16], equipped with a Kinova MICO arm (for pointing to and manipulating objects), an Xtion ASUS Pro camera (for viewing objects on tabletop surfaces), a Hokuyo lidar (for navigation and obstacle avoidance), a Blue Snowball microphone, and a speaker (for conducting the dialog). For this demonstration, speech transcripts are provided by the Google Speech API and speech synthesis is performed with the Festival Speech Synthesis System. Tabletop perception, required for both the dialog interaction and the execution of the resulting command, is implemented with RANSAC [9] plane fitting and Euclidean clustering as provided by Point Cloud Library [31].

5The demonstration video can be viewed at [https://youtu.be/PbOfteZ_CJc](https://youtu.be/PbOfteZ_CJc).

6[https://cloud.google.com/speech/](https://cloud.google.com/speech/)

R: What should I do?
H: Move a rattling container from the lounge by the conference room to Bob’s office.
R: Does rattling refer to a property of an object?
H: Yes.
R: Does rattling mean the same thing as empty?
H: No.
R: I am still learning the meanings of some words.
R: Show me an object you could use the word rattling when describing, or say “none of them.”
H: Watch. This one. The human picks up a small, full pill jar
R: I see.
R: Show me an object you could use the word rattling when describing, or say “none of them.”
H: Watch. This one. The human picks up a container half-full of beans
R: I see.
R: Thanks. Now back to business.
R: You want me to move an item from 3.514 to somewhere?
H: Yes.
R: I should move something from 3.514 to 3.510?
H: Yes.

(a) The human says move a rattling container.
(b) The robot asks questions about local items to learn rattling.
(c) The robot moves to the specified location.
(d) The robot decides which item is a rattling container and grasps it.
(e) The robot navigates to the specified destination room.
(f) The robot hands over the item at the specified destination.

Fig. 9: The agent learns a new word, rattling, which requires perception using the auditory sensing modality, and uses this new concept model to correctly identify and move the target item.

V. CONCLUSION

In this article, we presented a holistic system for jointly improving semantic parsing and grounded perception on a robotic system for interpreting natural language commands during human-robot dialog. We show, via a large-scale Mechanical Turk experiment, that users are better able to communicate tasks and rate the system more usable after this dialog-based learning procedure. We embody this learning agent in a physical robot platform to demonstrate its learning abilities for the non-visual word rattling.

We currently use the penultimate layer of the VGG network [32] as a sensorimotor context space for looking at objects, and in the future could similarly use auto-encoders over object representations [3] to provide a reduced feature vector representing a learned feature space for every sensorimotor context. There may be room for leveraging transfer learning between similarly-deployed robots (for example, in different hospitals) to increase the amount of human-robot language data available. This augmentation could enable learning more data-hungry, but less brittle, neural parsing methods [8].

ACKNOWLEDGEMENTS

This work was supported by a National Science Foundation Graduate Research Fellowship to the first author, an NSF EAGER grant (IIS-1548567), and an NSF NRI grant (IIS-1637736). This work has taken place in the Learning Agents Research Group (LARG) at UT Austin. LARG research is supported in part by NSF (CNS-1305287, IIS-1637736, IIS-1651089, IIS-1724157), TxDOT, Intel, Raytheon, and Lockheed Martin.
REFERENCES


[23] Cynthia Matuszek, Nicholas FitzGerald, Luke Zettlemoyer, Liefeng Bo, and Dieter Fox. A joint model of


[31] Radu Bogdan Rusu and Steve Cousins. 3D is here: Point Cloud Library (PCL). In IEEE International Conference on Robotics and Automation (ICRA), Shanghai, China, May 9-13 2011.


