



(A Monthly, Peer Reviewed, Refereed, Scholarly Indexed, Open Access Journal)



Impact Factor: 8.699

Volume 14, Issue 4, April 2025

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www.ijirset.com |A Monthly, Peer Reviewed & Refereed Journal| e-ISSN: 2319-8753| p-ISSN: 2347-6710|

Volume 14, Issue 4, April 2025

|DOI: 10.15680/IJIRSET.2025.1404511|

Collaborative Human-Robot Interaction in Dynamic Environments using Adaptive Learning Algorithms

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ABSTRACT: Robots must be able to work both independently and intelligently and adaptably with humans in order to be integrated into dynamic human environments like homes, factories, and hospitals. Using adaptive learning algorithms, this paper offers a thorough method for Collaborative Human-Robot Interaction (CHRI) in dynamic, uncertain environments. Robots can learn from human behavior, task contexts, and environmental changes in real time thanks to adaptive algorithms, which differ from static pre-programmed systems. In order to build robots that can recognize intentions, predict behavior, and adjust policies, we investigate the application of reinforcement learning, imitation learning, and meta-learning techniques. Through multi-modal perception and human feedback, the suggested architecture facilitates continuous learning and real-time decision-making. A number of simulations and real-world tests involving object manipulation, navigation, and collaboratively carrying out tasks. When compared to non-adaptive systems, the results show a notable improvement in task efficiency, human satisfaction, and interaction fluidity. The results highlight how adaptive learning can help develop human-robot teams that are genuinely cooperative, perceptive, and sensitive to context in uncertain settings.

KEYWORDS: Human-Robot Interaction (HRI),Collaborative Robotics, Adaptive Learning Algorithms, Reinforcement Learning, Imitation Learning, Meta-Learning, Dynamic Environments, Intention Recognition, Shared Autonomy, Real-Time Interaction, Robot Adaptation, Multi-Modal Perception, Human-Robot Collaboration, Machine Learning in Robotics, Interactive Robotics.

I. INTRODUCTION

Robotics has advanced beyond discrete industrial uses and is currently opening the door for integration with environments that are focused on people. In these situations, robots need to work well with humans in addition to automating tasks. Real-time coordination requirements, human behavior variability, and environmental unpredictability are some of the special difficulties that come with human-robot interaction (HRI) in dynamic environments.

Conventional HRI systems rely on pre-trained models or set rules, which frequently fail in dynamic environments where quick adaptation is essential. For example, a robot's incapacity to comprehend or react to unexpected changes can lead to inefficiencies or even safety hazards in collaborative assembly lines, elder care, or disaster response. As a result, adaptive learning algorithms become an essential tool that allow robots to continuously improve their human behavior models and the dynamics of the environment.

This paper uses adaptive learning techniques to propose a novel framework for collaborative human-robot interaction in dynamic environments. Our goal is to create proactive, not just reactive, robots that can comprehend intent, learn from mistakes, and adjust their behavior in real time.





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II. LITERATURE SURVEY

The Significant progress has been made by a number of researchers in enhancing HRI through machine learning: Robots can now learn the best policies in dynamic environments thanks to the widespread application of reinforcement learning, or RL. Notable research includes human-aware navigation [Tai et al., 2018] and deep reinforcement learning in robotic manipulation [Levine et al., 2016].

Imitation Learning (IL): IL is especially well-suited for tasks where human cooperation is essential because it enables robots to learn from expert demonstrations. DAgger, an interactive IL algorithm that increases policy robustness, was proposed by Ross et al. (2011).

Meta-Learning: Model-Agnostic Meta-Learning (MAML), which was presented by Finn et al. (2017), is a useful strategy for quickly adapting to new tasks in settings where task dynamics change frequently.

Collaborative Control Models: Goodrich and Schultz (2007) examined shared control tactics, highlighting adaptable autonomy based on task uncertainty and human feedback.

Adaptive, real-time learning mechanisms are frequently not integrated into existing systems within a coherent HRI framework, despite these advancements. By creating a cohesive architecture that integrates perception, reinforcement learning, and human feedback, our research fills this gap.

III. METHODOLOGY

3.1 Overview of the System

Three main parts make up the suggested CHRI system:

Perception Module: Multi-modal sensor fusion to track environmental conditions and human activity (vision, LiDAR, force sensors).

Learning Module: Uses adaptive algorithms to gradually improve behavior.

Voice, gestures, and haptic feedback are all supported by the interaction module.

3.2 Algorithms for Adaptive Learning

Reinforcement Learning (RL): For real-time policy learning and action selection, we use Proximal Policy Optimization (PPO).

Imitation Learning (IL): To bootstrap robot behavior, human collaborators' demonstrations are gathered.

Online learning: The model is updated continuously in response to fresh interactions.

Bayesian models are used to predict human intent and estimate uncertainty.

3.3 Collaboration Protocol Task Decomposition: Using capability analysis, tasks are divided into smaller tasks that are divided between the human and robot.

Recognition of Intent: Human intent is predicted from trajectory and gesture data using Bayesian inference.

Action Adaptation: In response to fresh information, adjustments, or human tactics, the robot adjusts its policy.

IV. EXPERIMENTAL RESULTS

4.1 Configuration

A UR5 robot and a mobile TurtleBot 3 were used in the experiments, which were carried out in both real-world and simulated environments (using Gazebo and ROS). The scenarios included:

tasks involving object handover.

cooperative movement through crowded areas.

Simple structures are assembled together.

4.2 Task Completion Time Metrics.

The time it takes to react to change is known as adaptation latency.

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Human Contentment (through post-task surveys). number of collisions or failures.



V. CONCLUSION

This research highlights the efficacy of adaptive learning algorithms in enhancing collaborative human-robot interaction within dynamic environments. By integrating reinforcement learning, imitation learning, and intent prediction into a unified system, robots can better understand and respond to the complexities of human behavior and environmental change. The experimental results validate our approach, showing improved efficiency, safety, and user satisfaction.Future work includes scaling the system for multi-agent collaboration, improving natural language communication, and deploying in long-term real-world scenarios such as smart homes and healthcare facilities.

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