



HAL
open science

Human-Robot Interaction in senior health care: a qualitative cases-study research on seniors experiencing a robot-coached functional rehabilitation exercise

Beatrice Le Gales-Garnett, Gilles Kermarrec, André Thépaut, Sao Mai Nguyen, Maxime Devanne, Olivier Rémy-Néris

► To cite this version:

Beatrice Le Gales-Garnett, Gilles Kermarrec, André Thépaut, Sao Mai Nguyen, Maxime Devanne, et al.. Human-Robot Interaction in senior health care: a qualitative cases-study research on seniors experiencing a robot-coached functional rehabilitation exercise. 2019. hal-02351086

HAL Id: hal-02351086

<https://hal.univ-brest.fr/hal-02351086>

Preprint submitted on 6 Nov 2019

HAL is a multi-disciplinary open access archive for the deposit and dissemination of scientific research documents, whether they are published or not. The documents may come from teaching and research institutions in France or abroad, or from public or private research centers.

L'archive ouverte pluridisciplinaire **HAL**, est destinée au dépôt et à la diffusion de documents scientifiques de niveau recherche, publiés ou non, émanant des établissements d'enseignement et de recherche français ou étrangers, des laboratoires publics ou privés.

1 **Human-Robot Interaction in senior health care: a qualitative cases-study research on seniors experiencing**
2 **a robot-coached functional rehabilitation exercise.**

3
4 Running title: **Robot coach from seniors' point-of-view.**

5
6 Affiliation and addresses of the authors

7 Béatrice Le Galès-Garnett (a) b.legalesgarnett@gmail.com, Gilles Kermarrec (a) Gilles.Kermarrec@univ-
8 brest.fr, André Thépaut (b) Andre.Thepaut@telecom-bretagne.eu, Sao Mai Nguyen (b) mai.nguyen@telecom-
9 bretagne.eu, Maxime Devanne (b) maxime.devanne@imt-atlantique.fr, Olivier Remy-Néris (c) olivier.remy-
10 neris@univ-brest.fr

11
12 (a) *CREAD, Research centre on education, learning process and didactic – Faculty of Sport Sciences and*
13 *Education, Bretagne-Loire University, Brest, France*

14
15 (b) *Lab-STICC, Laboratory for Sciences and Information Techniques, Communication and Knowledge,*
16 *Bretagne-Loire University, Brest, France*

17
18 (c) *La-TIM, Laboratory of Medical Information Processing, Bretagne-Loire University, Brest, France*

19
20
21 Corresponding author:

22 *Tel.:* +33 6 76 22 89 28

23 *E-mail address:* beatrice.legales@gmail.com

24 *Address:* 97 route de Toul ar hoat – 29470 LOPERHET, FRANCE

25
26 Corresponding Author: Béatrice Le Galès Garnett

27 ORCID ID : 0000-0002-7442-0062

28 Corresponding Author's Institution: p/o Dr Gilles Kermarrec, Ph.D., Senior Lecturer / CREAD, Research center
29 on education, learning process and didactic, Bretagne-Loire University, FRANCE.

30
31
32 **Compliance with Ethical Standards**

33 The authors declare that they have no conflict of interest. The authors declare the Research involves volunteer
34 human participants who have been fully informed and have provided written consents regarding their
35 participation to this Research programm.

36

37 **Abstract.** Telemedicine and assistive robot are an issue for aging well at home. This qualitative research
38 consisted in four study cases regarding elderly users experiencing a functional rehabilitation exercise coached by
39 an assistive robot. It focused on the inner concerns elicited during the Human-Robot-Interaction and their
40 evolution along the course of the experience. The data were collected and processed according to a course-of-
41 action analysis framework. The results showed that eight typical concerns shape the users' interactions with the
42 robot. This research highlighted that interacting with robots can produce a range of unexpected consequences
43 such as emotional, behavioural reactions, as well as some questions about identity. This might counteract the
44 initial design or even have a negative impact such as self-harm or rejection. One assumption guiding this work is
45 that the activity-oriented approach provides a new, specific and better understanding of a Human-Robot-
46 Interaction activity. This may provide guidelines for health and care roboticists and robotic interface designers. It
47 also draws attention to the role the social environment plays regarding Human-Robot-Interaction.

48

49 **Key-words:** user's experience; assistive robots; elderly; acceptability; motivation; course-of-action.

50 **1 Introduction**

51 The late Western World demography studies report a decreasing number of births (birth rate 4,9 in 1950, 2,47
52 today according to UNO) and longer life expectancy. Seniors aged 60 and more will represent 30% of the
53 population in 2030. This demographic evolution, together with a shortfall of nurses and caregivers plus the
54 health care cost, are the reasons why technology - and more specifically robotics – is being given increasing
55 attention (Broekens et al. 2009). Technology can provide therapy oversight, coaching and motivation (Okamura
56 et al. 2008). As an example, physical exercise has preventive effects on aging (Vuillemin 2012). It is widely
57 recommended to seniors wishing to age in place in order to maintain their autonomy. Robots, and particularly
58 assistive robots, have the potential to support physical activities in many ways. They are designed to be used at
59 home and assist some physical tasks an elderly person may not be able to do in full autonomy (e.g. getting up,
60 feeding, washing...). They also can promote physical and cognitive exercise (Görer et al. 2013). Some of these
61 robots can fulfill a combined role of coach and social companion in order to motivate (Obo et al. 2015). Recently
62 assistive robots have been designed to monitor the user during physical functional rehabilitation therapy
63 (N’Guyen et al. 2016). Thus, the aim of this exploratory study was to analyse the users’ experience during a
64 rehabilitation exercise program delivered by a robot coach to senior people. This work addresses a question of
65 crucial importance about the perception of robots by senior people, and about their potential coaching role in
66 functional rehabilitation exercise.

67

68 **2 State of the art**

69 **2.1 Research advances in human - robots interactions**

70 The implementation of new technology such as robots to support health care and physical activity have been
71 investigated, and recent research has provided evidence of positive outcomes. First, studies investigated the
72 effects of assistive social or companion-type robots on the health and wellbeing of the elderly living in nursing or
73 collective home. Some results showed positive outcomes on health variables such as mood or loneliness
74 (Broadbent, Stafford, MacDonald 2009), and some more positive effects on psychological variables such as
75 social connections and communication (Bemelmans, Gelderblom, Jonker, De Witte 2012). Second, a number of
76 studies showed the potential of robots to enhance engagement, motivation and physical activity (Fasola, Mataric
77 2013; Obo et al. 2015). Third, robots have been successfully used for rehabilitation (Fazekas et al. 2006;
78 Brewer et al. 2007). A recent study demonstrated that patients preferred the robot to a human assisting them with
79 the exercises (Cherry et al. 2016). Nevertheless, those positive outcomes depend on how people accept robot
80 interactions. Forth, the last decade has seen a number of studies focused on users' experiences of the robot
81 interactions (Anzalone et al. 2015). In psychology, socio-psychology and ergonomics, this type of research were
82 conducted within a variety of theoretical frameworks (Pino et al. 2015) used to understand user acceptance and
83 user behaviour of information technology. The Theory of Reasoned action (TRA) by Fishbein and Ajzen (1975)
84 pointed the link between behavioural aim and attitude. The Theory of planned behaviour (TPB) by Azjen (1985)
85 added three constructs predicting intentions : attitude, subjective norm, and perceived behavioural control
86 (Brown et Venkatesh 2005). The Technology Acceptance Model (TAM) (Davis 1989) has enhanced the
87 perceived usefulness, the ease of use and perceived ease of use (determinants of Perceived Ease of Use being
88 Integrating Control, Intrinsic Motivation and Emotion). The UTAUT model by Venkatesh, Thong and Xu
89 (2016), for Unified Theory of Acceptance and Use of Technology, has established that performance expectancy,
90 effort expectancy, as well as social influenced impacted on behavioural intention to use technology, whilst
91 behavioural intention and facilitating conditions determined technology use. The TAM model is today the most
92 commonly used model to investigate user acceptance of technology in health care (Broekens et al. 2009).

93 Advances in research showed that robot acceptance has proved to be an important issue among staff and patients
94 (Brewer et al. 2007). The success of such programs depends on users' acceptance (Chau et Osborne 2017).
95 Focusing on groups in many countries, Bedalf and al. (2016) suggested that older people are open to the idea of
96 having a robot supporting them in their daily life. A new insight to their acceptance of the robot is that they want
97 the robot to operate at the same level of intelligence as a human caregiver. Furthermore, the acceptance of robots
98 is culturally dependant (Broadbent et al. 2017) and perceived enjoyment (Heerik et al. 2008) is a source of
99 acceptance for robot companion. Gaps between needs and solutions offered by the robot and lack of experience
100 with technology have been identified as the most important barriers for robot acceptance (Pino et al. 2015).

101 Taken together, quantitative studies using TAM perspective pointed out that the users need to be aware of robots
102 potentialities, to accept them as opportunities and to make sense of robots behaviours or motions (Broadbent et
103 al. 2017). Though predictive, it is limited and does not provide sufficient understanding or information to create
104 user acceptance for new systems (Mathieson 1991). Thus, qualitative investigation of the human – robot
105 interaction (HRI) is needed.

106 **2.2 Qualitative investigation for HRI**

107 For over a century, qualitative researches have aimed at revealing, in a holistic approach, the sense-making
108 process, which results from the interaction of an human or participant with his natural environment. Qualitative
109 research explores the experiences of participants and the meaning they attribute to it. The aim of the qualitative
110 research is to observe, report, analyse and interpret the complexity of a dynamic phenomenon, which changes
111 continuously in response to prevailing conditions. Study case is still the dominant research method in qualitative
112 analysis. The qualitative approach considers a reality, which can be seen as constructed *by* a user rather than by a
113 designer *for* a user (italic added). The participant is active in the sense-making process. A qualitative approach
114 for HRI seems to be appropriate to answer questions such as what are seniors' concerns when they experiment a
115 robot designed to coach them rehabilitation activity? This study was conducted within the course-of-action
116 framework as a diachronic analysis of users concerns within a test situation setting an individual exercise session
117 coached by a Poppy robot.

118 Recent studies in psychology and ergonomics have investigated human - machine or objects interaction by
119 reconstructing how individual cognitions adjust over time (e.g., Poizat 2010). They use the theoretical and
120 methodological framework of the course-of-action, originally developed in the French language for research in
121 ergonomics (Theureau 2006) after Peirce's semiotic (1902), Merleau-Ponty's Phenomenology of perception
122 (1945) and Varela and Maturana's *autopièse* (1974) and *enaction* (1987) concepts. The method involves
123 resetting of the participant in the initial activity using its material traces such as auto-confrontation video
124 methods. The aim of these methods is to lead the participants to elicit their pre-reflexive consciousness. A major
125 component of pre-reflexive consciousness is the focus on the dynamic of the participants concerns. Within the
126 framework, a concern refers to participants' interests, focuses or perceptions and/or intentions. Concerns can be
127 defined and specified at any given instant regarding what makes sense or contributes to sense making for the
128 participant. If we assume that an participant concern orients his/her situated activity as related to a specific
129 moment, time and environment then an investigation of such concerns and their categorization into typical
130 concerns can be expected to describe the emotional and cognitive experience of each participant.

131

132 **3 Method**

133 This qualitative approach complies with the recommended report standards (O'Brien et a. 2014).

134 **3.1 Participants and setting**

135 The size of the sample was an empiric choice. The participants consisted of 4: one woman and three men (M age
136 = 70, SD = 9). They will be designated as A, B, C and D, and collectively as the participants or the actors. None
137 had any previous experience of exposure to any assistive robot. This robot was a 3D humanoid Poppy robot
138 conceptualized by INRIA laboratory, France. It was visibly a moving mechanical object (exposed plastic parts,
139 mini-motors, screws, nuts and wires). At that point of its development it had no expression and no capacity of
140 interacting with its environment. The participants were selected according to three *criteria* related to health care
141 assistive robots potential users: (1) aged 60+ (aged from 60 to 79), (2) living at home in a rural environment, and
142 (3) no known or obvious cognitive mental decline. D had had a stroke five years before, and still suffered from a
143 left shoulder and arm movement deficiency. D was looked after by a medical team, part of whom stood in the
144 test room during the test. A simple description of the robot had been given to A, B and C the day before the test :
145 “*The robot looks like a mechanic Lego, or a Meccano, it is rather small, just the top part, it will not talk*”. They
146 were given a consent form to read, fill up and sign as well as an authorization for the use of their image for
147 scientific purposes to which they fully and with no reserve subscribed to. The setting of the test meant to
148 reproduce the conditions of a senior ageing at home and living alone. Four video cameras were placed in the test
149 room in order to capture the robot as well as the participant’s motion. The test involved a multidisciplinary team
150 of ergonomics scientists, medical scientists, computer scientists (CS), physiotherapists and engineers
151 collaborating in designing the study case. The CS team needed to compare two different 3D capture motions
152 equipment to find out which would be best for a future evolution of the Poppy robot to detect and measure the
153 difference between the movements shown by the robot and the one performed by the participants. An important
154 consequence of this multidisciplinary test was that the participants were asked to wear sensors and other bits of
155 equipment before starting the test. They rather enjoyed “*looking like a robot*”. A second consequence was that
156 there were 4 video cameras and up to 7 people gathered in the test room.

157 **3.2 Procedure**

158 First, the robot had to be programmed to be able to demonstrate a movement. One possible way was to code a
159 specific program. The alternative we chose was for the researcher to manipulate the robot and perform the
160 required movements while they were being computer-recorded. Therefore, by pressing “play”, the student in
161 charge would make the robot execute the movement. The test consisted of seven different sets of movements
162 defined by the multidisciplinary staff. Only the torso and the arms were involved. The motion had been planned
163 to be realistic enough to map human gestures and was progressively more difficult to perform. The general
164 sequence involved an one-arm gesture, then a symmetrical repetition of the movement with the other arm, then the
165 use of the two arms simultaneously. Some movements were horizontal, others were vertical. They were some up-
166 liftings, pushings and circles makings. The last one was a leaning and bending on one side with an up-lifted arm
167 above the head bending the same way. The student explained to the participant that the robot would perform one
168 sequence whilst the participant, who was seated facing the robot, would observe. Then the robot would repeat the
169 sequence and this time the participant would copy it. There would be a pause between each sequence, due to the
170 time required to record then bring the robot back to its original posture and set the next sequence. For each
171 participant, the test followed the same pattern and lasted approximately a half hour. Apart from occasional visits
172 from the lab director and the CS supervisors, the student and the researcher were handling the test. The medical
173 team (doctor, physiotherapist) stepped in the lab only for D.

174 **3.3 Data collection**

175 The data were collected according to a procedure defined by the course-of-action methodology (Theureau
176 2006). Two types of data were gathered: (a) non-verbal data, based on video recordings of the participants’
177 behaviour during the sequences (see Photo I below) and ethnological observations written down by the
178 researcher and (b) verbal-data, informal for some, formal for others, collected in the course of the tests and some
179 pre- and post-tests interviews, among which a self-confrontation interview (see Photo II below) This later
180 consisted for each participant in viewing his/her own test-film and stopping the video at any time whilst
181 watching it, in order to show, explain, mime or comment on it. The researcher conducted the interview and could
182 also stop the video and question the participant. The questions, according to Theureau’s theory, dealt with the
183 “Actual”, that is what was happening and perceived in this course-of-action, with questions such as “*How do you*
184 *feel now? What are you aware of? What are you doing here?*“. Another range of questions deal with what
185 Theureau calls “Potential”, that is to say what was expected to happen, might happen, was wished or feared. This
186 was related to questions such as “*What do you think would happen next? What were you expecting? What did*
187 *you intend to do here?*“. The self-confrontation interviews were filmed. One camera was settled so as to capture
188 the screen on which the film of the test was played, as well as the participant watching it. To minimize the
189 possibility that the participants would forget, inference or generalize about their thinking, the interviews were
190 conducted within 24 to 72 hours after the test. The interviews lasted between an hour and an hour and a half
191 each. This technique of self-confrontation interview is designed to account for the level of activity that is
192 meaningful to the participant and the emergence of their pre-reflexive consciousness that guides their activity.

193

194

195

Photo I about here

196

Photo II about here

197

198 **3.4 Data processing**

199 All the verbal exchanges, which occurred between the participants and the main researcher during the interviews,
200 were then fully transcribed in a four columns board names Table I.

201

202

Table I about here

203

204 One column was related to the time precisely quoted to match the following columns, the second contained the
205 *verbatim* of what had occurred during the experience. The third column contained the *verbatim* of the self-
206 confrontation interview. The last column consisted in ethnographic notes and photos taken by the researcher
207 during the test and/or the self-confrontation interview. The data were then processed in four steps: (a) identifying
208 discrete sense-making units, (b) categorizing these units into typical concerns (what the participants focused on),
209 (c) ensuring trustworthiness of the data and analysis (d) analysing temporal evolution of typical concerns.

210 **3.5 Identifying meaningful units**

211 Data were processed by selecting discrete meaningful units. These units are assumed to be the expression of the
212 participant’s experience (Theureau 2006). They were feelings, focuses, perceptions, actions and
213 communications. During the exercise sequence, a total of 242 such discrete units were identified: 72 units for A,
214 28 units for B, 101 units for C and 34 units for D.

215 **3.6 Categorizing the meaningful units into typical concerns**

216 An analysis of the successive participants' concerns enabled them to be organized into more general categories
217 of similar types of concerns, that is to say typical concerns. They were distinguished on the basis of three
218 *criteria*: a) the meaning of each category of typical concern, b) the same level of generality across the categories,
219 and c) a label sufficiently discriminating to avoid overlap (Corbin et Strauss 2008). The categories were defined
220 one by one. A new category was created each time a concern did not match an existing category or when a
221 sufficient number of units pointed to a common and specific concern. Eight categories of typical concerns were
222 identified.

223 **3.7 Coding the categories**

224 A code was given to every single unit. (i.e: C6-S3-AC2-09:57). It reported the category number, the participant
225 name, the designation of the film and the time the Unit occurred in the film. The purpose of it being to data-
226 visualize the relationship between the evolution of the concerns and the exercises progression in time. (See
227 Figure I below).

228 **3.8 Coding the time line**

229 T0 stood for the time before exercise 1 started. T1 stood for the time to perform exercise 1 and so on. T8 stood
230 for the time following the end of exercise 7. (See Figure I below).

231 **3.9 Trust worthing the data and analysis**

232 To ensure the credibility of the data categorization two trained investigators processed them. These two
233 researchers had already coded protocols of this type in earlier studies, and were familiar with course-of-action
234 theory. The reliability of the coding procedure was assessed using Bellack's agreement rate (Van Someren,
235 Barnard, Sandleberg 1994). The initial agreement rated 83% for the categorization of typical concerns. Any of
236 these initial disagreements were resolved by discussion between the researchers. They debated their
237 interpretations until a consensus was reached regarding the number of categories and their labelling. Finally,
238 agreement rate reached 98%.

239

240 **4 Results**

241 This section is divided into three parts: (a) the eight typical concerns, (b) the dynamic of concerns during the
242 exercise sequences, and (c) four cases focus on the human-robot interaction.

243 **4.1 Typical concerns**

244 First, the analysis revealed that the four participants shared eight typical concerns experienced during the course
245 of their interaction with the robot. The concerns were designated as C followed by a concern category number
246 from 1 to 10 (see Table II). The ones which gathered the most important number of units were : C3 - to self-
247 evaluate oneself (33 units) ; C5 - to catch up with speed, the rhythm (33 units) ; C7 - to notice or admit a
248 difficulty (30 units) ; C8 - to notice a human-robot difference (29 units).

249 -----

250 Table II about here

251 -----

252 **4.2 Dynamic of concerns during the exercise sequence**

253

254 The Figure I (see below) showed that some concerns (C3, C5), not all, were expressed all along the test.

255 -----
256 Figure I about here
257 -----

258 The spectrum of concerns also started at a high range: T1 started with 39 units and T2 with 71 units. Most
259 concerns had a peak moment: C1 at T1 and T2, C5 and C7 at T2, C3 at T4 regarding the participants' focuses
260 and interactions at that moment in time. A peak of concerns rose at T2 but for C2 and C4.

261 The specific exercise required at T2 was an horizontal lift-up movement of the upper-arm whilst the elbow was
262 kept loose. This exercise had to be performed by one arm, then the other, then two arms simultaneously. It had
263 been planned to be "second" in term of difficulty in the progress of the sequences. All participants faced
264 ergonomic difficulties to perform it, some found it unusual, unnatural or "*never to be asked*". A wide range of
265 unexpected concerns raised: speed, self-evaluation, starting time, emotions, robot identity, the nature of the task.
266 After the peak, the concerns generally lowered and smoothed towards the end of the exercise. Six units were
267 registered at T5, 14 at T6 and 25 units at T7.

268

269 **4.3 Four cases focus of a human-robot interaction**

270 According to the course-of-action framework, singular and personal experiences emerge from the coupling of the
271 environment with each participant's previous experience. The data revealed that though the purpose of the test
272 was announced in the same way to the four participants, each one experienced a different situation according to
273 one's perception of this human-robot interaction. The following part of this paper defines each participant's
274 experience then presents some unexpected aspects of the complexity of the situation that was studied.

275 *4.3.1 Various profiles of engagement*

276 Participant A focused on moving at the robot's rhythm and speed (16 units) and on starting just at the same time
277 (8 units). This required a lot of efforts (9 units). A main categories profile was: C5-C8-C4. B focused on the
278 difficulty B met (10 units) on copying the movement (5 units) and on all that prevented B from copying right (4
279 units). B main categories profile was: C7-C1-C6. C was hugely concerned by self-evaluation (25 units). C
280 wanted to perform and focused on finding ways of catching up with the speed (13 units), noticing all the
281 differences (11 units) which might have helped him/her not to be surprised and be able to anticipate (11 units). C
282 main categories profile was: C3-C5-C6-C8. Finally, D focused on the difficulties he/she met (10 units) to simply
283 copy the movements (8 units). The differences between D and the robot enhanced them (6 units). D main
284 categories profile was: C7-C1-C6. This results showed how specifically each participant interacted with what
285 was supposed to be a similar situation.

286 *4.3.2 The test recalled emotional memories*

287 C (aged 76) took an RAF pilot test fifty years ago and failed for “lack of reflexes”. A reason he/she never
288 subscribed to, being an athlete. C still felt he/she had to prove being quick enough and they were wrong at the
289 time. C competed with the robot and with oneself. C : “An awful lot of things physical that I’ve done in my life
290 have been done euh because... when you’re told you’re not good enough to be an RAF pilot, that sits with you
291 for the rest of your life”, “there you are, with a lot of technicians around you and you get in to know unfamiliar
292 equipment and put on unfamiliar clothes and, and then, you, you know you’re not gonna crash it, are you ?”, “I
293 could make a mess of the test... by just simply not managing to do it properly”. Though C was fifty years older
294 this early experience of failure put C under pressure in order to catch up and never be late especially since no
295 sign and no indication was given about when to start or stop, time had not mentioned as being an issue.

296 4.3.3 *The test challenged unexpectedly*

297 B (aged 79) attended a senior gym class on a regular basis and felt quite fit. He/She faced difficulty trying to
298 copy the second exercise and was not happy with it. B: “*It’s hard but these are not, these are not movements one*
299 *would normally do*”, “*I practise gym, gym for seniors, and we do not do these kind of movements. And I think*
300 *our coach is pretty qualified herself*”. He/She accepted personal failure but blame the robot for its lack of
301 competency in comparison with what a real professional gym coach would do.

302 4.3.4 *The test questioned the identity of the robot*

303 The participants designated the robot as “Poppy”, “the robot”, “ the computer” or “the machine”. D: “*the robot*
304 *does it, well it is programed to do so of course, so it does it naturally*”, A: “*I had dehumanized the robot, I was*
305 *just noticing the mechanical part of it*”, “*We had to twitch ours arms there, for the robot that was somehow*
306 *difficult to do*”, C: “*the way that robot comes to rest is particularly robotic*”. When the test was done, D kissed
307 the robot goodbye for D liked it, found it was a “*smart little one*”.

308 4.3.5 *The test raised human identity questions*

309 Interacting with the robot led the participants to reflexive questions about what they were really doing, what they
310 were really asked to do, and even whom they were, regarding to whom they thought they were. A: “*I had to*
311 *overcome this personal challenge*”. C had to succeed, for “*physical problem might lead to mental problems*
312 *about physical competence*”, “*if you want to love someone you must first of all love yourself. And if you wish*
313 *them to love you then you must be lovable, physical competence is... is important, at any age*”. B: “*I noticed it*
314 *was... more flexible than me !*”. C: “*There are some elements of competitiveness. Whichever can do this better?*
315 *Me or the machine?*”.

316 4.3.6 *The test raised ambiguity*

317 The dynamic of the relation – who imitates who? - as well as the adjustment to the machine produced questions
318 and doubts.

319 C : “*Do I have to imitate the robot or is the robot imitating me?*”, “*Was I expecting to take copy of every tiny*
320 *movement Poppy made? Or was I expected to copy the general movement? That Poppy made?*”, “*It’s just that,*
321 *just that you have to imitate a limited joint movement with a much more flexible joint movement.*”

322 4.3.7 *The test reveals a need for guidance and reassurance.*

323 Participants suggested that the HRI should be mediated. *C did not hear well: “that’s another instruction that I*
324 *missed. Or wasn’t made clear.” B: “Oh well, if I had been put there on my own, I may not have felt that proud,*
325 *no, no; having people around makes you feel all right.”. D: “I was trying to meet somebody’s eyes, I was trying*
326 *to know if I was ok, if somebody would raise the thumb up to mean “yes, great”, I was not looking for*
327 *compliments but some encouragement to pursue”.*

328 As a result of the *couplage* (Theureau 2004; 2006) in the enaction process, these singular experiences revealed
329 the Human-Robot-Interaction complexity and raised unexpected reactions regarding to the aim of exercise.

330

331 **5 Discussion**

332 Because exercise is medicine, and robotics used in health care offer resources for sustaining physical activity
333 (e.g., Fasola et Mataric 2013), this exploratory study investigated participants’ experiences in a rehabilitation
334 exercise session coached by a robot. It focused on the types of concerns elicited during their experience. As a
335 result, the study cases of four seniors showed that a) eight typical concerns impacted their interactions with the
336 robot, b) the concerns evolved within the progression of the experience, as in a learning process, c) each
337 participant had a singular experience regarding robot acceptance. These results furnish insights about the
338 potentialities and the limits of robots used to coach physical exercise to the elderly. The results are hereafter
339 discussed according to three points that could address new insight for acceptance: robots sustain motivation;
340 learning the task and the robot’s use; and contributions for designers.

341 **5.1 Motivation: Robots challenge us**

342 Previous research demonstrated that robots have the potential to enhance motivation and physical activity (Obo
343 et al. 2015), and that perceived enjoyment (Heerik et al. 2008) is a source of acceptance for robot companion.
344 Our results showed how a robot coaching experience could motivate senior people. In this study, A and C were
345 motivated to perform the task, while B was challenged by a personal cognitive difficulty and D by a physical
346 deficiency. Complementary, motivation came from the test conditions: the sharing of the experience, the clothes
347 change, with equipment and sensors (to wear for the motion capture test taking place at the same time) that made
348 them look a little robotic themselves. By analysing the recovery-from-stroke-situations using assisting robots,
349 Cherry and al. (2016) demonstrated that patients preferred the robot to a human assisting them with the
350 exercises, despite technical and ergonomic difficulties. Here, D trying hard to do as good as possible worried the
351 physiotherapist who thought D would harm oneself by reaching too wide an amplitude according to D’s
352 capacity. D was aware and paid attention to the difficulty but not as much to the stress put on her/his body.

353 A robot is far from being a neutral coach for physical activity. The use of robots as technological artefacts to
354 provide physical activity needs more investigation in order to understand how it could sustain motivation for
355 exercise, and what kind of motivation sustain acceptance.

356 **5.2 Learning the task and the robot’s use**

357 A few studies suggest that robots are effective for physiotherapy (Fazekas et al. 2006), or that old people provide
358 better assessment of the physical robot coach compared to virtual systems (Fasola et Matarić 2013). In this study,
359 the effectiveness of the movement learning process was not assessed. Nevertheless, many concerns aimed at
360 learning, and performing the movements the robot demonstrated. Regarding the evolution of the main concern
361 (39 units in T1, 71 units in T2, down to 6 units in T5), an hypothesis can be made that the participants learnt the
362 movements as well as they learnt to deal with the robot, so that they elicited less typical concerns about efforts,
363 emotions with on-going the course of action. It could be hypothesized from the dynamic of concerns that HRI
364 provides a learning situation with transform the actor's activity.

365 One major difficulty the participants concerns revealed may be interpreted as a consequence of
366 anthropomorphism. When trying to understand or interact with an unfamiliar non-human agent, people use their
367 knowledge of themselves as a basis for understanding these entities (Broadbent 2017). They try to recognize
368 human attitude or movement behind the robot. B: *“There you had to swirl its arms so the robot could perform
369 that movement. It has motors, not articulations, he is not as flexible as us”*. In this study, C6 could be considered
370 as a consequence of this anthropomorphic tendency. D: *“The robot is quite closed to the movement to
371 demonstrate”*. Because old people want the robot to manifest the same level of intelligence as a human coach
372 (Bedaf and al. 2016) in this study they provided advices for next design process. Broadbent (2017) showed that
373 the more social agent a robot is planned to be, the more it has to perceive and understand human behaviour on
374 top of acting in a human like way to favour acceptance. The appearance of the robot (shape, face, eye contact,
375 tune of voice) will depend on the task, and the expectation the person has of a human performing that task. Thus,
376 based on our results, anthropomorphism could indeed be a design principle to support acceptance in HRI.

377 **5.3 Contribution to assistive robot design**

378 Qualitative studies provide insights on complex phenomenon such as human-robot interaction during learning
379 and performing a movement sequence. Such research in ergonomics also aims at providing feedback for
380 designers and developers (Theureau 2006). Because gaps between needs and solutions offered by the robot have
381 been identified as the most important barriers for robot acceptance (Pino et al. 2015), our results should furnish
382 precious information. Especially, the main typical concerns (C3, C5, C7, C8) provide information, which would
383 be useful for robot designing and robot-coaching situation setting and using. First, one way to favour the use of
384 such a robot would be to eliminate all sources of ambiguity, regarding identity, tasks, expectations, aims, issues
385 and coherence of tasks... The less ambiguity, the less questions that may detract from the purpose of the exercise.
386 To evaluate the potential ambiguity of such an interaction, a guide or question form would need to be conceived
387 and tested. A second way of favouring acceptance would be to limit the stress due to the situation by reducing or
388 eliminating any kind of competition or challenge between the human user and the robot. A solution may be to
389 reinforce the authority of the user over the robot that should be able to choose the task difficulty or the exercise
390 levels. The suppression of ambiguities would also contribute to lower the stress level. A third way would be to
391 prepare the users to share feelings, emotions and reactions, even unexpected ones. The interest of such
392 perspective to enhance robot acceptance would require further inquiries.

393

394 **6 Conclusion**

395 In this study, some results have confirmed that acceptance is linked to personal factors such as motivation and
396 self-esteem. Results also provided insight about how to develop seniors' acceptance for assistive robots.
397 Nevertheless, a common charge against case study research is that its findings are not generalizable. Advocates
398 of case study respond to this by arguing that case study gives access to the inner lives of people, to the emergent
399 properties of social interaction, and/or to the underlying mechanisms which generate human behaviours (Gomm
400 et al. 2000). Though one case produces a small piece of evidence, the repetition of observations across a series of
401 cases can build a database of evidences, and shape theory in an inductive way (Meganck et al. 2017).
402 Furthermore, new researches with a larger sample are needed to verify how robots' potentialities and behaviours
403 impact users' learning and performing.

404 Future study could complete the first-person point of view with a third-person point of view. According to Poizat
405 and al. (2012) first-person data is suitable for retracing the dynamics of individuals' lived experience, whereas
406 third-person data could help the researcher to highlight behaviours or constraints that could not spontaneously be
407 described by actors. For an example, the biomechanical measures could help us to compare the gap between the
408 movement the robot demonstrated and the movement the patient did (N'Guyen et al. 2018). Finally, by
409 combining qualitative and quantitative analysis, future research could provide significant issues on the
410 relationships between robots' artefacts and users' experiences.

411

412 **Bibliography**

- 413 Anzalone SM, Boucenna S, Ivaldi S, Chetouani M (2015) Evaluating the Engagement with Social Robots.
414 *International Journal of Social Robotics*, 7(4), pp 465–478. <https://doi.org/10.1007/s12369-015-0298-7>
- 415 Ajzen I (1985) From Intentions to Actions: A Theory of Planned Behavior. In: Kuhl J., Beckmann J. (eds)
416 *Action Control*. SSSP Springer Series in Social Psychology. Springer, Berlin
- 417 Barbier J-M (2011) *Vocabulaire d'analyse des activités*. PUF, Paris
- 418 Bedaf S, Draper H, Gelderblom G-J, Sorell T, de Witte L (2016) Can a Service Robot Which Supports
419 Independent Living of Older People Disobey a Command ? The Views of Older People, Informal Carers
420 and Professional Caregivers on the Acceptability of Robots. *International Journal of Social Robotics*, 8
421 (3), pp 409–420. <https://doi.org/10.1007/s12369-016-0336-0>
- 422 Bemelmans R, Gelderblom GJ, Jonker P, De Witte (2012) Socially assistive robots in elderly care: a systematic
423 review into effects and effectiveness. *Journal of the American Medical Directors Association*. 13(2), pp
424 114-120. <https://doi.org/10.1016/j.jamda.2010.10.002>
- 425 Brewer B R, McDowell S K, Worthen-Chaudhari L C (2007) Poststroke Upper Extremity Rehabilitation: A
426 Review of Robotic Systems and Clinical Results. *Topics in Stroke Rehabilitation*, 14(6), pp 22–44.
427 <https://doi.org/10.1310/tsr1406-22>
- 428 Broadbent E (2017) Interactions With Robots: The Truths We Reveal About Ourselves. *Annual Review of*
429 *Psychology*, Vol. 68, pp 627-652. <https://doi.org/10.1146/annurev-psych-010416-043958>
- 430 Broadbent E, Stafford R, MacDonald B (2009) Acceptance of Healthcare Robots for the Older Population:
431 Review and Future Directions. Springer, Netherlands
- 432 Broekens J, Heerink M, Rosendal H (2009) Assistive social robots in elderly care: a review. *Gerontechnology*,
433 8(2). <https://doi.org/10.4017/gt.2009.08.02.002.00>

434 Brown A, Venkatesh V (2005) Household Technology Use: Integrating household life cycle and the Model of
435 Adoption of technology in Households. *MIS Quarterly* Vol. 29 No. 3/pp 399-426
436 <https://doi.org/10.2307/25148690>

437 Chau D, Osborne T F (2017) *Using technology to improve care of older adults*. Springer, New-York

438 Cherry C O et al (2015) Expanding stroke tele-rehabilitation services to rural veterans: a qualitative study on
439 patient experiences using the robotic stroke therapy delivery and monitoring system program. *Disability
440 and Rehabilitation: Assistive Technology*, 1–7. <https://doi.org/10.3109/17483107.2015.1061613>

441 Corbin J, Strauss A (2008) *Basics of Qualitative Research : Techniques and Procedures for Developing
442 Grounded Theory* (3rd ed.), Sage publications Inc, Los Angeles, CA

443 Davis F D (1989) Perceived Usefulness, Perceived Ease of Use, and User Acceptance of Information
444 Technology. *MIS Quarterly*, 13(3), pp 319. <https://doi.org/10.2307/249008>

445 Fasola J, Matarić M (2013) A Socially Assistive Robot Exercise Coach for the Elderly. *Journal of Human-
446 Robot Interaction*, 2(2). <https://doi.org/10.5898/jhri.2.2.fasola>

447 Fazekas G, Horvath M, Toth A (2006) A novel robot training system designed to supplement upper limb
448 physiotherapy of patients with spastic hemiparesis. *International Journal of Rehabilitation Research*,
449 29(3), pp 251–254. <https://doi.org/10.1097/01.mrr.0000230050.16604.d9>

450 Fishbein M, Ajzen I (1975) *Belief, Attitude, Intention, and Behavior: An Introduction to Theory and Research*.
451 Madison-Wesley, Reading, MA

452 Görer B, Salah A A, aAkin H L (2013) A Robotic Fitness Coach for the Elderly. *Ambient Intelligence*, pp124–
453 139. https://doi.org/10.1007/978-3-319-03647-2_9

454 Heerink M, Kröse B, Evers V, Wielinga B (2006) Studying the acceptance of a robotic agent by elderly users.
455 *International Journal of Assistive Robotics and Mechatronics*, 2006b. 7(3), p 33-43.
456 <https://doi.org/10.1109/roman.2006.314442>

457 McCreadie C, Tinker A (2005) The acceptability of assistive technology to older people. *aging and Society*,
458 25(01), pp 91–110. <https://doi.org/10.1017/s0144686x0400248x>

459 Meganck R et al (2017) Empirical Single Case Studies in Psychoanalysis. *Frontiers in Psychology*. Volume 8.
460 Article 1749. <https://doi.org/10.3389/fpsyg.2017.01749>

461 Merleau-Ponty M (1945) *Phénoménologie de la perception*. Paris, Gallimard

462 N’Guyen S M, Tanguy P, Rémy-Néris O (2016) Computational architecture of a robot coach for physical
463 exercises in kinaesthetic rehabilitation. 25th IEEE International Symposium on Robot and Human
464 Interactive Communication, pp1138-1143. <https://doi.org/10.1109/roman.2016.7745251>

465 O’Brien B et al (2014) Standards for reporting qualitative research: a synthesis of recommendations. *Academic
466 medicine*, Vol.89, No.9. <https://doi.org/10.1097/ACM.0000000000000388>

467 Obo T, Loo C K, Kubota N (2015) Imitation learning for daily exercise support with robot partner. 24th IEEE
468 International Symposium on Robot and Human Interactive Communication, pp 752-757. <https://doi.org/10.1109/roman.2015.7333695>

470 Okamura A, Matarić M, Christensen H (2010) Medical and Health-Care Robotics. *IEEE Robotics & Automation
471 Magazine*, 17(3), pp 26–37. <https://doi.org/10.1109/mra.2010.937861>

472 Peirce C S (1902) *Logic as Semiotic: The Theory of Signs*. Philosophical Writings. Dover Publications, Dover

473 Pino M, Boulay M, Jouen F, Rigaud A-S (2015) “Are we ready for robots that care for us?” Attitudes and
474 opinions of older adults toward socially assistive robots. *Frontiers in Aging Neuroscience*, 7.
475 <https://doi.org/10.3389/fnagi.2015.00141>

476 Poizat G, Adé D, Seifert L, Toussaint H, Gal-Petitfaux N (2010) Evaluation of the Measuring Active Drag
477 system usability: An important step for its integration into training sessions. *International Journal of*
478 *Performance Analysis in Sport*, 10(2), pp 170–186. <https://doi.org/10.1080/24748668.2010.11868512>

479 Theureau J (2010) Les entretiens d'autoconfrontation et de remise en situation par les traces matérielles et le
480 programme de recherche « cours d'action ». *Revue d'anthropologie des connaissances*, 4(2), pp 287-322.
481 <https://doi.org/10.3917/rac.010.0287>.

482 Theureau J (2006) *Le cours d'action : Méthode développée*. Toulouse, Octarès Editions

483 Varela F G, Maturana H, Uribe R (1974) Autopoiesis: The organization of living systems, its characterization
484 and a model, *BioSystems*, Vol. 5, pp 187-196. [https://doi.org/10.1016/0303-2647\(74\)90031-8](https://doi.org/10.1016/0303-2647(74)90031-8)

485 Varela F G, Maturana H (1987) *The tree of knowledge: the biological roots of human understanding*. Shambala,
486 Boston & London

487 Venkatesh V (2000) Determinants of Perceived Ease of Use: Integrating Control, Intrinsic Motivation, and
488 Emotion into the Technology Acceptance Model. *Information Systems Research*. Vol. 11, No. 4. <https://doi.org/10.1287/isre.11.4.342.11872>

489

490 Venkatesh V, Morris MG, Davis GB, et Davis FD (2003) User Acceptance of Information Technology: Toward
491 a Unified View. *MIS Quarterly*, 27(3), p 425. <https://doi.org/10.2307/30036540>

492 Venkatesh V, Thong J Y L, Xu X (2016) Unified Theory of Acceptance and Use of Technology: A Synthesis
493 and the Road Ahead. *Journal of the Association for Information Systems*. Volume 17- Issue 5, pp 328–
494 376. ISSN : 1536-9323

495 Vuillemin A (2012) Bénéfices de l'activité physique sur la santé des personnes âgées. *Science & Sports*, 27(4),
496 pp 249–253. <https://doi.org/10.1016/j.scispo.2012.07.006>

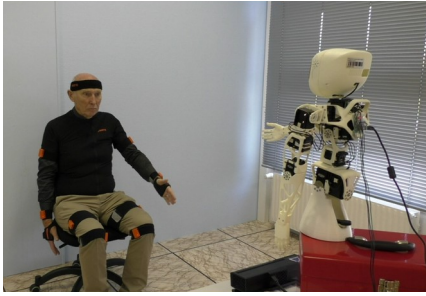
497



498 **Annexes**

499 **Photo files**

500 Photo I. C attends the test.



502 Photo II. C attends the self-confrontation interview.

503
504
505
506
507
508
509




510 **Table files**

511 Table I. The four columns board

512

Time	Verbatim of the activity	Verbatim of the self-confrontation	Ethnographic notes and photogram
------	--------------------------	------------------------------------	----------------------------------

03:25	<p>D : « je vais vous montrer l'exercice 2 »</p> <p>Poppy montre exo 2.</p> <p>S4 monte le bras D et plie son coude</p>	<p>18:23 Par contre la rotation je vous dis euh, surtout regardez l'autre là-bas (il montre robot)18:35 Ouais c'est celui là que j'avais du mal. Parce que lui montait son avant-bras comme ça (il mime) et moi je pouvais, je pouvais pas (il plie son coude D, se ravise, change de bras) j'étais comme ça là (il plie son coude G).</p>	<p>A : (mouvement de tête, ne semble pas satisfait de son mouvement)</p> 
-------	---	--	--

Concern category number	Category name (units number)	Meaningful units
C1	to perform the task well (27)	<i>"I was told I was to copy the movement of the machine. So copy the movements of the machine means copy the movements of the machine !...machine does it you do it" , "Indeed you just had to copy what it did"</i>
C2	to deal with personal emotions (17)	<i>Is it a matter of personal pride that you can manage this kind of thing ? I am an able bodied person I am not, you know, hm, Physically pretty competent and I would aim not to make a mistake in this kind of thing", "I was mainly afraid I would not succeed", "if you miss, you are quite annoyed and I don't like it"</i>
C3	to self-evaluate (33)	<i>"So I'm not giving myself more than 6 out of ten for this" , "Well, I have uplifted my arms too high, see, I haven't observed properly"</i>
C4	to keep producing an effort (13)	<i>"I concentrated very hard on seeing how, how the robot moves.", "One minute was enough for then you were quite happy to relax again", "I'm fairly well involved in the task"</i>
C5	to catch up with the speed, the rhythm (33)	<i>"The speedier the movement is, the riskier it is to make a mistake and not copy exactly", " it's to be in time...that was the exercise", "the rhythm was not too fast", "sometimes I would slow down then to catch up the pace I had to speed up (sigh)"</i>
C6	to notice a human-robot difference (29)	<i>"there for instance I've bended the elbow whereas there's no bend in the elbow at all", "Because the robot is not a human skeleton, right, does the human skeleton imitate the robotic skeleton or is the robotic skeleton imitating the human skeleton ?", " It has motors, not joints, not as souple as us"</i>
C7	to identify a difficulty (30)	<i>"No I can't bend my elbow the way it does it, no I can't. Can anyone do by the way ? ", "In that movement you see there are different rotations which go on in way which doesn't go on in you arm. Or don't go in mine anyway."</i>
C8	to try not to be surprised (21)	<i>"one is on the alert. What's gonna happen next ?", "When one does it for the first time, on might be surprised", "There may be a bit of confusion, there, see ? the movement is quite sudden"</i>