The **Neurodivergent Scale for Interacting with Robots (NSIR)** can be used as a valuable evaluation tool for the **Echo-Teddy** project described in the Lee et al. (2026) paper.

The Echo-Teddy article focuses on the preliminary design of a social robot, powered by a large language model (LLM), aimed at supporting the social interaction skills of autistic students. The NSIR provides the user-centric metrics to assess if this design successfully achieves its goals across three key dimensions:

Anthropomorphic Connection/Kinship

- The Echo-Teddy project is developing an expressive social robot designed to be engaging for autistic students.
- NSIR items like **"The robot is more like me than anyone else I know"** and **"I gave my robot a name"** (p. 1) can measure the effectiveness of the design in fostering a personal bond and perceived companionship, which is crucial for a therapeutic robot.

Social Comfort/Trust

- The LLM in Echo-Teddy is intended to facilitate "effective communication" and social skills training, aiming to build a comfortable and predictable interaction environment.
- The NSIR items that measure perceived emotional understanding and consistency (e.g., **"My robot can tell what I am feeling, when I am sad, it can tell I am sad"**, and **"I believe that my robot is the same with me as it is with anyone"**) (p. 1) directly assess the user's experience of the robot's social intelligence and reliability.

Safety

- The design of any robot interacting with a vulnerable population requires careful consideration of safety and ethical boundaries.
- The NSIR's **safety** dimension provides a mechanism to ensure that as the robot's social interaction capabilities become more advanced (via LLMs), users still feel secure and their personal boundaries are respected (e.g., the item about feeling comfortable undressing in front of the robot) (p. 1).

The NSIR allows the researchers of the Echo-Teddy project to move beyond technical performance metrics and gather essential data on the quality and impact of the user's experience.

Would you like to examine how the scale might apply to another article from the document, or maybe compare the design approach of **Echo-Teddy** to another robot?