The claims defining the invention are as follows:

1. A human interaction system for interaction by a user comprising social systems comprising at least a social robot and one or more virtual robot systems, and a coordination system, wherein:

the social robot is controlled by a robot processing system and is configured to provide interaction with a user, said interaction including output means and input means,

the one or more virtual robot systems are configured to controllably present an avatar representation of the social robot, and further configured to receive inputs,

the coordination system is configured to coordinate operation of the social robot and the one or more virtual robots such that, at any one time, either the social robot or one of the virtual robot systems is active, wherein when the social robot is inactive, the social robot is configured not to undertake functions corresponding to a personality associated with the social robot and when the one or more virtual robot systems are inactive, the one or more virtual robot systems are configured to not present the avatar representation of the social robot,

the coordination system is configured to determine a location of a user in an environment and in the event that the social robot is active and the determined location of the user is closer to a display than to the social robot or one of the virtual robot systems is active and the determined location of the user is closer to another display than to the display that presents an avatar representation of the social robot, to respectively present an avatar representation of the social robot on the display or on the other display,

such that, in operation, a user perceives the robot personality associated with the social robot and the avatar as associated with the active social robot or virtual robot system.

2. The system as claimed in claim 1, wherein the social robot comprises at least one of:

one or more cameras and/or a microphone as input means;

a speaker and/or one or more lights as output means; and

a first portion, such as a head, moveable with respect to a second portion, such as a body.

3. The system as claimed in any one of claims 1 to 2, wherein the coordination system is configured to:

communicate a message to the respective virtual robot system displayed on the display or on the other display configuring it as active.

4. The system as claimed in claim 3, wherein the coordination system is further configured to communicate a message to the virtual robot system displayed on the display or on the other display configuring it as inactive.

5. The system as claimed in any one of claims 1 to 4, wherein the one or more virtual robot systems are configured to animate the avatar, and wherein at least one animation is equivalent to a movement of the social robot.

6. The system as claimed in any one of claims 1 to 5, wherein the robot processing system is configured to control, at least in part, the operation of an active virtual robot system.

7. The system as claimed in claim 6, wherein the active virtual robot system is configured to interpret commands received from the robot processing system and adapt said commands for display on a display of the virtual robot system.

8. The system as claimed in any one of claims 1 to 7, where at least one virtual robot system is configured with at least two predefined avatar appearances, and wherein one of said predefined avatar appearances is selected in dependence on an application.

9. The system as claimed in claim 8, wherein one of the at least two predefined avatar appearances is a neutral appearance.

10. The system as claimed in any one of claims 1 to 9, further comprising one or more interaction devices in data communication with the social robot and/or the one

or more virtual robot systems, the interaction devices enabling the user to provide inputs and receive outputs.

11. The system as claimed in claim 10, wherein at least one virtual robot system is configured to present a virtual object corresponding to one of the one or more interaction devices.

12. The system as claimed in any one of claims 1 to 11, wherein the avatar appearance is controllable in response to a user command to perform a verbal communication and/or a visual action.

13. A human interaction system for interaction by a user comprising social systems comprising at least a social robot and one or more virtual robot systems, wherein:

the social robot is controlled by a robot processing system and is configured to provide interaction with a control user, said interaction including output means and input means, the social robot being configured to be active or inactive,

the one or more virtual robot systems are configured to controllably present an avatar representation of the social robot, and further configured to receive inputs, wherein the, or each, virtual robot system is associated with a user, each of the one or more virtual robot systems being configured to be active or inactive,

the coordination system is configured to determine a location of a user in an environment and in the event that the social robot is active and the determined location of the user is closer to a display than to the social robot or one of the virtual robot systems is active and the determined location of the user is closer to another display than to the display that presents an avatar representation of the social robot, to respectively present an avatar representation of the social robot on the display or on the other display,

such that, in operation, the, or each, user perceives a robot personality associated with the social robot and the avatar as associated with the active social robot or virtual robot system, wherein when the social robot is inactive, the social robot is configured not to undertake functions corresponding to a personality associated with the social robot and when the one or more virtual robot systems are

inactive, the one or more virtual robot systems are configured to not present the avatar representation of the social robot.

14. The system as claimed in claim 13, wherein the one or more virtual robot systems are configured to animate the avatar, and wherein at least one animation is equivalent to a movement of the social robot and at least one animation is not equivalent to a movement of the social robot.

15. The system as claimed in any one of claims 13 to 14, further comprising one or more interaction devices in data communication with the social robot and/or virtual robot system(s), the interaction devices enabling the user to provide inputs and receive outputs.

16. The system as claimed in claim 13, wherein at least one virtual robot system is configured to present a virtual object corresponding to an interaction device.

17. The system as claimed in claim 13, wherein the social robot is configured to receive voice commands from the control user, wherein at least one voice command corresponds to a request for information from a particular virtual robot system, and wherein the social robot is further configured to communicate said command to said particular virtual robot system.

18. The system as claimed in claim 17, wherein at least one virtual robot system is further configured to:

receive a directed command;

undertake an associated action; and

communicate a response to the social robot.

19. The system as claimed in claim 18, wherein at least one associate action comprises obtaining a result from an associated auxiliary device in communication with the associated virtual robot system.

20. A human interaction method for allowing interaction by a user with a social system comprising at least a social robot and one or more virtual robot systems, comprising:

controlling the social robot to provide interaction with a user, said interaction including output means and input means,

controllably presenting an avatar representation of the social robot on one or more displays, such that when an avatar representation is displayed on a display it is active,

coordinating operation of the social robot and the one or more virtual robots such that, at any one time, either the social robot or one of the virtual robot systems is active, wherein when the social robot is inactive, the social robot is configured not to undertake functions corresponding to a personality associated with the social robot and when the one or more virtual robot systems are inactive, the one or more virtual robot systems are configured to not present the avatar representation of the social robot,

coordinating operation of the social robot and the one or more virtual robots to determine a location of a user in an environment and in the event that the social robot is active and the determined location of the user is closer to a display than to the social robot or one of the virtual robot systems is active and the determined location of the user is closer to another display than to the display that presents an avatar representation of the social robot, to respectively present an avatar representation of the social robot on the display or on the other display,

such that, in operation, a user perceives a robot personality associated with the social robot and the avatar as associated with the active social robot or virtual robot system.