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Raja Chatila (Eds.)**

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The Eleventh International Symposium

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**Oussama Khatib, Vijay Kumar, Daniela
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simultaneous localization and mapping SLAM for autonomous robots which has been receiving a great deal of attention by the research community in the latest few years The contents are focused on the autonomous mapping learning problem Solutions include uncertainty driven exploration active loop closing coordination of multiple robots learning and incorporating background knowledge and dealing with dynamic environments Results are accompanied by a rich set of experiments revealing a promising outlook toward the application to a wide range of mobile robots and field settings such as search and rescue transportation tasks or automated vacuum cleaning

Robotics Science Michael Brady, 1989 These 16 contributions provide a field guide to robotics science today These 16 contributions provide a field guide to robotics science today Each takes up current work the problems addressed and future directions in the areas of perception planning control design and actuation In a substantial introduction Michael Brady summarizes a personal list of 30 problems problem areas and issues that lie on the path to development of a science of robotics These involve sensing vision mobility design control manipulation reasoning geometric reasoning and systems integration Contents

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Robotics Science is included in the System Development Foundation Benchmark series System Development Foundation grants have contributed significantly to the development of robotics in the United States during the 1980s

Proceedings of the 11th International Conference on Modelling, Identification and Control (ICMIC2019) Rui Wang, Zengqiang Chen, Weicun Zhang, Quanmin Zhu, 2019-12-03 This book includes original peer reviewed research papers from the 11th International Conference on Modelling Identification and Control ICMIC2019 held in Tianjin China on July 13 15 2019 The topics covered include but are not limited to System Identification Linear Nonlinear Control Systems Data driven Modelling and Control Process Modelling and Process Control Fault Diagnosis and Reliable Control Intelligent Systems and Machine Learning and Artificial Intelligence The papers showcased here share the latest findings on methodologies algorithms and applications in modelling identification and control integrated with Artificial Intelligence AI making the book a valuable asset for researchers engineers and university students alike

Algorithmic Foundation of Robotics VII Srinivas Akella, Nancy M. Amato, Wesley

Huang, Bud Mishra, 2008-07-10 Algorithms are a fundamental component of robotic systems they control or reason about motion and perception in the physical world They receive input from noisy sensors consider geometric and physical constraints and operate on the world through imprecise actuators The design and analysis of robot algorithms therefore raises a unique combination of questions in control theory computational and differential geometry and computer science This book contains the proceedings from the 2006 Workshop on the Algorithmic Foundations of Robotics This biannual workshop is a highly selective meeting of leading researchers in the field of algorithmic issues related to robotics The 32 papers in this book span a wide variety of topics from fundamental motion planning algorithms to applications in medicine and biology but they have in common a foundation in the algorithmic problems of robotic systems **FastSLAM** Michael Montemerlo, Sebastian Thrun, 2007-04-27 This monograph describes a new family of algorithms for the simultaneous localization and mapping SLAM problem in robotics called FastSLAM The FastSLAM type algorithms have enabled robots to acquire maps of unprecedented size and accuracy in a number of robot application domains and have been successfully applied in different dynamic environments including a solution to the problem of people tracking **Algorithmic Foundations of Robotics VIII** Gregory S. Chirikjian, Howie Choset, Marco Morales, Todd Murphey, 2010-02-04 This book contains selected contributions to WAFR the highly competitive meeting on the algorithmic foundations of robotics They address the unique combination of questions that the design and analysis of robot algorithms inspires **The DARPA Urban Challenge** Martin Buehler, Karl Iagnemma, Sanjiv Singh, 2009-11-11 By the dawn of the new millennium robotics has undergone a major transformation in scope and dimensions This expansion has been brought about by the maturity of the field and the advances in its related technologies From a largely dominant industrial focus robotics has been rapidly expanding into the challenges of the human world The new generation of robots is expected to safely and dependably co-habitat with humans in homes workplaces and communities providing support in services entertainment education healthcare manufacturing and assistance Beyond its impact on physical robots the body of knowledge robotics has produced is revealing a much wider range of applications reaching across diverse research areas and scientific disciplines such as biomechanics haptics neurosciences virtual simulation animation surgery and sensor networks among others In return the challenges of the new emerging areas are proving an abundant source of stimulation and insights for the field of robotics It is indeed at the intersection of disciplines that the most striking advances happen The goal of the series of Springer Tracts in Advanced Robotics STAR is to bring in a timely fashion the latest advances and developments in robotics on the basis of their significance and quality It is our hope that the wider dissemination of research developments will stimulate more exchanges and collaborations among the research community and contribute to further advancement of this rapidly growing field

Proceedings of 2021 5th Chinese Conference on Swarm Intelligence and Cooperative Control Zhang Ren, Mengyi Wang, Yongzhao Hua, 2022-07-29 This book includes original peer reviewed research papers from the 2021 5th Chinese

Conference on Swarm Intelligence and Cooperative Control CCSICC2021 held in Shenzhen China on January 19 22 2022 The topics covered include but are not limited to reviews and discussions of swarm intelligence basic theories on swarm intelligence swarm communication and networking swarm perception awareness and location swarm decision and planning cooperative control cooperative guidance swarm simulation and assessment The papers showcased here share the latest findings on theories algorithms and applications in swarm intelligence and cooperative control making the book a valuable asset for researchers engineers and university students alike

Software Engineering for Experimental Robotics Davide Brugali, 2007-04-16 Software Engineering for Experimental Robotics collects contributions that describe the state of the art in software development for the Robotics domain It reports on innovative ideas that are progressively introduced in the software development process in order to promote the reuse of robotic software artifacts domain engineering components frameworks and architectural styles It illustrates the results of the most successful and well known research projects which aim to develop reusable robotic software systems Most of the chapters report on concepts and ideas discussed at the well attended ICRA2005 Workshop on Principles and Practice of Software Development in Robotics Barcelona Spain April 18 2005 The authors are recognised as leading scholars internationally and the result is an effective blend of fundamental and innovative results on research and development in software for robotic systems where one common factor is the integration of reusable building blocks Besides the advancement in the field most contributions survey the state of the art report a number of practical applications to real systems and discuss possible future developments

Algorithmic Foundations of Robotics XI H. Levent Akin, Nancy M. Amato, Volkan Isler, A. Frank van der Stappen, 2015-04-30 This carefully edited volume is the outcome of the eleventh edition of the Workshop on Algorithmic Foundations of Robotics WAFR which is the premier venue showcasing cutting edge research in algorithmic robotics The eleventh WAFR which was held August 3 5 2014 at Bo azi i University in Istanbul Turkey continued this tradition This volume contains extended versions of the 42 papers presented at WAFR These contributions highlight the cutting edge research in classical robotics problems e g manipulation motion path multi robot and kinodynamic planning geometric and topological computation in robotics as well novel applications such as informative path planning active sensing and surgical planning This book rich by topics and authoritative contributors is a unique reference on the current developments and new directions in the field of algorithmic foundations

Correct Reasoning Esra Erdem, Joohyung Lee, Yuliya Lierler, David Pearce, 2012-06-03 This Festschrift published in honor of Vladimir Lifschitz on the occasion of his 65th birthday presents 39 articles by colleagues from all over the world with whom Vladimir Lifschitz had cooperation in various respects The 39 contributions reflect the breadth and the depth of the work of Vladimir Lifschitz in logic programming circumscription default logic action theory causal reasoning and answer set programming

On Motion Planning Using Numerical Optimal Control Kristoffer Bergman, 2019-05-28 During the last decades motion planning for autonomous systems has become an important area of research The high interest is not the least due to

the development of systems such as self driving cars unmanned aerial vehicles and robotic manipulators In this thesis the objective is not only to find feasible solutions to a motion planning problem but solutions that also optimize some kind of performance measure From a control perspective the resulting problem is an instance of an optimal control problem In this thesis the focus is to further develop optimal control algorithms such that they be can used to obtain improved solutions to motion planning problems This is achieved by combining ideas from automatic control numerical optimization and robotics First a systematic approach for computing local solutions to motion planning problems in challenging environments is presented The solutions are computed by combining homotopy methods and numerical optimal control techniques The general principle is to define a homotopy that transforms or preferably relaxes the original problem to an easily solved problem The approach is demonstrated in motion planning problems in 2D and 3D environments where the presented method outperforms both a state of the art numerical optimal control method based on standard initialization strategies and a state of the art optimizing sampling based planner based on random sampling Second a framework for automatically generating motion primitives for lattice based motion planners is proposed Given a family of systems the user only needs to specify which principle types of motions that are relevant for the considered system family Based on the selected principle motions and a selected system instance the algorithm not only automatically optimizes the motions connecting pre defined boundary conditions but also simultaneously optimizes the terminal state constraints as well In addition to handling static a priori known system parameters such as platform dimensions the framework also allows for fast automatic re optimization of motion primitives if the system parameters change while the system is in use Furthermore the proposed framework is extended to also allow for an optimization of discretization parameters that are are used by the lattice based motion planner to define a state space discretization This enables an optimized selection of these parameters for a specific system instance Finally a unified optimization based path planning approach to efficiently compute locally optimal solutions to advanced path planning problems is presented The main idea is to combine the strengths of sampling based path planners and numerical optimal control The lattice based path planner is applied to the problem in a first step using a discretized search space where system dynamics and objective function are chosen to coincide with those used in a second numerical optimal control step This novel tight combination of a sampling based path planner and numerical optimal control makes in a structured way benefit of the former method s ability to solve combinatorial parts of the problem and the latter method s ability to obtain locally optimal solutions not constrained to a discretized search space The proposed approach is shown in several practically relevant path planning problems to provide improvements in terms of computation time numerical reliability and objective function value

Human-in-the-Loop Robot Control and Learning Luka Peternel, Jan Babič, Erhan Oztop, Tetsunari Inamura, Dingguo Zhang, 2020-01-22 In the past years there has been considerable effort to move robots from industrial environments to our daily lives where they can collaborate and interact with humans to improve our life quality One of the

key challenges in this direction is to make a suitable robot control system that can adapt to humans and interactively learn from humans to facilitate the efficient and safe co existence of the two The applications of such robotic systems include service robotics and physical human robot collaboration assistive and rehabilitation robotics semi autonomous cars etc To achieve the goal of integrating robotic systems into these applications several important research directions must be explored One such direction is the study of skill transfer where a human operator s skilled executions are used to obtain an autonomous controller Another important direction is shared control where a robotic controller and humans control the same body tool mechanism car etc Shared control in turn invokes very rich research questions such as co adaptation between the human and the robot where the two agents can benefit from each other s skills or must adapt to each other s behavior to achieve effective cooperative task executions The aim of this Research Topic is to help bridge the gap between the state of the art and above mentioned goals through novel multidisciplinary approaches in human in the loop robot control and learning

Electroactive Polymer Gel Robots Mihoko Otake, 2010-03-10 By the dawn of the new millennium robotics has undergone a major transformation in scope and dimensions This expansion has been brought about by the maturity of the field and the advances in its related technologies From a largely dominant industrial focus robotics has been rapidly expanding into the challenges of the human world The new generation of robots is expected to safely and dependably co habitat with humans in homes workplaces and communities providing support in services entertainment education health care manufacturing and assistance Beyond its impact on physical robots the body of knowledge robotics has produced is revealing a much wider range of applications reaching across diverse research areas and scientific disciplines such as biomechanics haptics neurosciences virtual simulation animation surgery and sensor networks among others In return the challenges of the new emerging areas are providing an abundant source of stimulation and insights for the field of robotics It is indeed at the intersection of disciplines that the most striking advances happen The goal of the series of Springer Tracts in Advanced Robotics STAR is to bring in a timely fashion the latest advances and developments in robotics on the basis of their significance and quality It is our hope that the wider dissemination of research developments will stimulate more exchanges and collaborations among the research community and contribute to further advancement of this rapidly growing field

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