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Sommario/riassunto	The goal of this work is to provide building blocks for resource-aware robot architectures. The topic of these blocks are data-driven generation of context-sensitive resource models, prediction of future resource utilizations, and resource-aware computer vision and motion planning algorithms. The implementation of these algorithms is based on resource-aware concepts and methodologies originating from the Transregional Collaborative Research Center ""Invasive Computing"" (SFB/TR 89).