

1. Record Nr.	UNINA9910969915503321
Titolo	Robotics : science and systems VII / / edited by Hugh Durrant-Whyte, Nicholas Roy, and Pieter Abbeel
Pubbl/distr/stampa	Cambridge, MA, : MIT Press, ©2012
ISBN	9786613806383 9781282133808 1282133802 9780262305969 0262305968
Edizione	[1st ed.]
Descrizione fisica	1 online resource (382 p.)
Altri autori (Persone)	Durrant-WhyteHugh F. <1961-> RoyNicholas AbbeelPieter
Disciplina	629.8/92
Soggetti	Robotics
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	Description based upon print version of record.
Nota di bibliografia	Includes bibliographical references.
Nota di contenuto	Contents; Preface; Organizing Committee; Program Committee; Workshop Evaluation Committee; Sponsors; Unmanned Aircraft Collision Avoidance Using Continuous-State POMDPs; I. INTRODUCTION; II. RELATED WORK; III. COLLISION AVOIDANCE MODELS; IV. MONTE CARLO VALUE ITERATION (MCVI); V. SIMULATION RESULTS; VI. DISCUSSION; VII. CONCLUSIONS; REFERENCES; Identification and Representation of Homotopy Classes of Trajectories for Search-Based Path Planning in 3D; I. INTRODUCTION; II. BACKGROUND; III. APPLICATION OF THEORY OF ELECTROMAGNETISM IN IDENTIFYING HOMOTOPY CLASSES IV. SEARCH-BASED PLANNING IN THREE DIMENSIONS WITH HOMOTOPY CLASS CONSTRAINTSV. RESULTS; VI. HOMOLOGY AS AN APPROXIMATION OF HOMOTOPY; VII. CONCLUSION; REFERENCES; Controlling Wild Bodies Using Linear Temporal Logic; I. INTRODUCTION; II. THE OVERALL DESIGN; III. CONTROLLING ONE WILD BODY; IV. CONTROLLING MULTIPLE WILD BODIES; V. EXPERIMENTS; VI. CONCLUSIONS AND FUTURE WORK; REFERENCES; Exploiting Variable

Stiffness in Explosive Movement Tasks; I. INTRODUCTION; II. OPTIMAL TORQUE/STIFFNESS CONTROL; III. CASE STUDY: OPTIMAL BALL THROWING  
 IV. EXPLOITING VARIABLE STIFFNESS THROUGH OPTIMAL CONTROLV. BALL THROWING EXPERIMENT; VI. CONCLUSION; ACKNOWLEDGMENTS; REFERENCES; Automatic Calibration of Multiple Coplanar Sensors; I. INTRODUCTION; II. BACKGROUND; III. PROBLEM STATEMENT; IV. OBSERVABILITY & THE CRAMER-RAO LOWER BOUND; V. ESTIMATION; VII. INTERPOLATION IN PRACTICE; VIII. PRACTICAL COVARIANCE MEASUREMENTS; IX. RESULTS; X. CONCLUSION; APPENDIX; REFERENCES; A Linear Approximation for Graph-Based Simultaneous Localization and Mapping; I. INTRODUCTION; II. RELATED WORK; III. PROBLEM FORMULATION  
 IV. A LINEAR ESTIMATION FRAMEWORK FOR SLAMV. EXPERIMENTAL VALIDATION; VI. CONCLUSION; ACKNOWLEDGMENTS; REFERENCES; The Motion Grammar: Linguistic Perception, Planning, and Control; I. INTRODUCTION; II. RELATED WORK; III. THE MOTION GRAMMAR; IV. GRAMMARS FOR ROBOTIC SYSTEMS; V. HUMAN-ROBOT GAME APPLICATION; VI. ANALYSIS; VII. CONCLUSIONS AND FUTURE WORK; REFERENCES; Learning to Control a Low-Cost Manipulator Using Data-Efficient Reinforcement Learning; I. INTRODUCTION; II. RELATED WORK; III. PRELIMINARIES; IV. POLICY LEARNING WITH STATE-SPACE CONSTRAINTS; V. EXPERIMENTAL VALIDATION  
 VI. DISCUSSIONVII. CONCLUSION; ACKNOWLEDGEMENTS; REFERENCES; A Framework for Push-Grasping in Clutter; I. Introduction; II. Planning Framework; III. Action Library; IV. Implementation and Results; V. Conclusion and Discussion; Acknowledgments; References; Infinite-Horizon Model Predictive Control for Periodic Tasks with Contacts; I. INTRODUCTION; II. RELATED WORK; III. BACKGROUND; IV. WHY MPC IS NOT ENOUGH; V. INFINITE-HORIZON MODEL PREDICTIVE CONTROL; VI. APPROXIMATING THE INFINITE HORIZON VALUE FUNCTION; VII. RESULTS; VIII. CONCLUSION; APPENDIX; REFERENCES  
 An Art Gallery Approach to Ensuring That Landmarks Are Distinguishable

## Sommario/riassunto

Robotics: Science and Systems VII spans a wide spectrum of robotics, bringing together researchers working on the algorithmic or mathematical foundations of robotics, robotics applications, and analysis of robotics systems. This volume presents the proceedings of the seventh annual Robotics: Science and Systems conference, held in 2011 at the University of Southern California. The papers presented cover a wide range of topics in robotics, spanning mechanisms, kinematics, dynamics and control, human-robot interaction and human-centered systems, distributed systems, mobile systems and mobility, manipulation, field robotics, medical robotics, biological robotics, robot perception, and estimation and learning in robotic systems. The conference and its proceedings reflect not only the tremendous growth of robotics as a discipline but also the desire in the robotics community for a flagship event at which the best of the research in the field can be presented.