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1999 Ieee International Conference On Robotics And Automation

Daniela Rus, Sanjiv Singh



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1999 IEEE International Conference on Robotics and Automation ,1999 **1999 IEEE International Conference on Robotics and Automation** IEEE Robotics and Automation Society Staff,IEEE Robotics and Automation Society,IEEE,1999 The theme of the 1999 IEEE International Conference on Robotics and Automation ICRA99 conference is Mega Information Integration for Robots and Automation in the 21st Century In the coming century applications in robotics and automation must acquire greater flexibility if they are to yield better products at higher efficiency To this end enormous amounts of information must be integrated in robotics add automation technologies These include large scale sensor integration human machine coordination virtual reality representation roboterized table top factory dynamic process planning and control information based scheduling enterprise level modeling and analysis supply chain management and more Proceedings, 1999 IEEE International Symposium on Computational Intelligence in Robotics and Automation ,1999 This volume documents and contextualizes the conflicting representations of rural life during a crucial period of social economic and cultural change It highlights the dialogues and tensions between agriculture and aesthetics economics and morality men and women leisure and labour By drawing on both canonical and marginal texts it argues that early modern writing not only reflected but played a part in constructing the cultural meanings of the English countryside with which we continue to live

International Symposium on History of Machines and MechanismsProceedings HMM 2000 Marco Ceccarelli,2013-11-11 The International Symposium on History of Machines and Mechanisms is a new initiative to promote explicitly researches and publications in the field of the History of TMM Theory of Machines and Mechanisms It was held at the University of Cassino Italy from 11 to 13 May 2000 The Symposium was devoted mainly to the technical aspects of historical developments and therefore it has been addressed mainly to the IFToMM Community In fact most the authors of the contributed papers are experts in TMM and related topics This has been indeed a challenge convincing technical experts to go further in depth into the background of their topics of expertise We have received a very positive response as can be seen by the fact that these Proceedings contain contributions by authors from all around the world We received about 50 papers and after review about 40 papers were accepted for both presentation and publishing in the Proceedings This means also that the History of TMM is of interest everywhere and indeed an in depth knowledge of the past can be of great help in working on the present and in shaping the future with new ideas I believe that a reader will take advantage of the papers in these Proceedings with further satisfaction and motivation for her or his work historical or not These papers cover the wide field of the History of Mechanical Engineering and particularly the History of TMM **RAMSETE** Salvatore Nicosia,Bruno Siciliano,Antonio Bicchi,Paolo Valigi,2003-07-01 Robotics applications initially developed for industrial and manufacturing contexts are now strongly present in several elds Besides well known space and high technology applications robotics for every day life and medical s vices is becoming more and more popular As an example robotic manipu tors are particularly

useful in surgery and radiation treatments they could be employed for civil demining for helping disabled people and ultimately for domestic tasks entertainment and education Such a kind of robotic applications require the integration of many different skills Autonomous vehicles and mobile robots in general must be integrated with articulated manipulators Many robotic technologies sensors actuators and computing systems must be properly used with specific technologies localisation planning and control technologies The task of designing robots for these applications is a hard challenge a specific competence in each area is demanded in the effort of a truly integrated multidisciplinary design

Sensor Based Intelligent Robots Gregory D. Hager, Henrik I. Christensen, Horst Bunke, Rolf Klein, 2003-08-06 Robotics is a highly interdisciplinary research topic that requires integration of methods for mechanics control engineering signal processing planning graphics human computer interaction real time systems applied mathematics and software engineering to enable construction of fully operational systems The diversity of topics needed to design implement and deploy such systems implies that it is almost impossible for individual teams to provide the needed critical mass for such endeavors To facilitate interaction and progress on sensor based intelligent robotics interdisciplinary workshops are necessary through which depth discussion can be used for cross dissemination between different disciplines The Dagstuhl foundation has organized a number of workshops on Modeling and Integration of Sensor Based Intelligent Robot Systems The Dagstuhl seminars take place over a full week in a beautiful setting in the Saarland in Germany The setting provides an ideal environment for in depth presentations and rich interaction between the participants This volume contains papers presented during the fourth workshop held tober 15 20 2000 All papers were submitted by workshop attendees and were reviewed by at least one reviewer We wish to thank all of the reviewers for their invaluable help in making this a high quality selection of papers We gratefully acknowledge the support of the Schloss Dagstuhl Foundation and the staff at Springer Verlag Without their support the production of this volume would not have been possible

Climbing and Walking Robots and the Supporting Technologies for Mobile Machines G. Muscato, D. Longo, 2003-11-07 Bringing together academics researchers and industrialists Climbing and Walking Robots 2003 CLAWAR 2003 provides a forum for cross fertilization in the different specialities so that both state of the art and industrial applications can be reported on Original contributions both industrial and those in new emerging fields provide a full picture of climbing and walking robots The interest in climbing and walking robots CLAWAR has increased considerably over recent years addressing many application fields such as exploration intervention in extreme environments personal services emergency rescue operations transportation entertainment etc and envisage humanoid robots evolving into mechatronic replicas of ourselves Topics covered include Biological Inspired Systems Medical Systems Control of CLAWAR Design Methodology System Modelling and Simulation Modularity and System Architecture Gait Generation and Stability of CLAWAR Biped Locomotion Multi legged Locomotion Micro Machines Applications Climbing Robots Actuators Sensors Navigation and Sensors Fusion CLAWAR Network Workpackages

Advanced Control Methods in Marine Robotics Applications Fabio Bonsignorio, Enrica Zereik, Marco Bibuli, Kristin Ytterstad Pettersen, Oussama Khatib, 2021-06-09

A Stable and Transparent Framework for Adaptive Shared Control of Robots Ribin Balachandran, 2023-12-28

Robotic research and developments in computing technologies including artificial intelligence have led to significant improvements in autonomous capabilities of robots. Yet human supervision is advisable and in many cases necessary when robots interact with real world outside lab environments. This is due to the fact that complete autonomy in robots has not yet been achieved. When robots encounter challenges beyond their capabilities, a viable solution is to include human operators in the loop who can support robots through teleoperation, taking complete control or shared control. This monograph focuses on a special form of shared control, namely mixed initiative, where the final command to the robot is a weighted sum of the commands from the operator and the autonomous controller. The weights, fixed or adaptive, called authority allocation (AA) factors, decide who has more control authority over the robot. Several research groups use different methods to adapt the AA factors online, and the benefits of adaptive mixed initiative shared control have been well established in terms of task completion success and operator usability. However, stability of the overall shared control framework with communication time delays between the operator and the robot is a field that has not been examined extensively. This monograph presents methods to improve performance and stability in shared control so that the possibilities of its applications can be widened. Firstly, methods to improve the haptic feedback performance of teleoperation are developed. Secondly, methods to stabilize adaptive shared control systems while still ensuring high teleoperation performance are proposed. The methods are validated on multiple robotic systems and they were applied in several projects both in space and terrestrial domains. With the aforementioned contributions, this monograph provides an overarching framework to improve synergy between humans and robots. The flexibility of the framework allows integration of existent teleoperation and shared control approaches, which further promotes synergy within the robotics community.

3D Scene Modeling and Robotics Interaction Xin Yang, Baocai Yin, Xiaopeng Wei, 2025-05-18

This book focuses on the intelligent perception and interaction module in intelligent robotic systems. It establishes a multidisciplinary cross-fertilization knowledge system, explores the related technology frontiers and research frontiers as comprehensively as possible from the perspective of scene modeling and understanding, and develops a practical exposition of practical application tasks such as robotic navigation, obstacle avoidance, and grasping. The main contents of this book include 3D reconstruction, scene exploration, scene understanding, robot navigation and obstacle avoidance, robot grasping, and comprehensive project practice. Combining theory and practice, the book contains both basic algorithms and covers the latest technologies with detailed code or pseudo-code resources. This book can be used as a teaching reference book for information and intelligence-related majors in higher education institutions, computer graphics, computer vision, and intelligent robotics, and other related fields, as well as a reference book for technicians engaged in related fields. This book takes intelligent robots as the carrier, focuses on the

technologies of environment perception and understanding and applying them to practical tasks such as robot navigation obstacle avoidance and grasping The book consists of six chapters Chapters 1 to 3 provide a comprehensive introduction to the development and application of scene modeling and understanding technologies including 3D reconstruction scene exploration and scene understanding Chapters 4 and Chapter 5 provide a comprehensive introduction to the development and application of robot perception technologies including visual relocalization and robot navigation obstacle avoidance and grasping Chapter 6 introduces comprehensive project practice with 3D scene modeling and understanding for robot tasks as an example which facilitates readers to have a comprehensive understanding and mastery of theory and practice The translation was done with the help of artificial intelligence A subsequent human revision was done primarily in terms of content

Robot Manipulators Alex Lazinica,Hiroyuki Kawai,2010-04-01 Robot manipulators are developing more in the direction of industrial robots than of human workers Recently the applications of robot manipulators are spreading their focus for example Da Vinci as a medical robot ASIMO as a humanoid robot and so on There are many research topics within the field of robot manipulators e g motion planning cooperation with a human and fusion with external sensors like vision haptic and force etc Moreover these include both technical problems in the industry and theoretical problems in the academic fields This book is a collection of papers presenting the latest research issues from around the world

Experimental Robotics VII Daniela Rus,Sanjiv Singh,2007-09-04 Experimental robotics is at the core of validating robotics research for both its system science and theoretical foundations Robotics experiments serve as a unifying theme for robotics system science and theoretical foundations This book collects papers on the state of the art in experimental robotics The papers were presented at the 2000 International Symposium on Experimental Robotics

Visual Perception and Robotic Manipulation Geoffrey Taylor,Lindsay Kleeman,2008-08-18 This book moves toward the realization of domestic robots by presenting an integrated view of computer vision and robotics covering fundamental topics including optimal sensor design visual servo ing 3D object modelling and recognition and multi cue tracking emphasizing robustness throughout Covering theory and implementation experimental results and comprehensive multimedia support including video clips VRML data C code and lecture slides this book is a practical reference for roboticists and a valuable teaching resource

Intelligent Transportation Vehicles Max Suell Dutra,Omar Lengerke,2011-09-09 Intelligent transportation vehicles brings the latest advances and developments in intelligent vehicles to readers on the basis of their significance and quality 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 This Ebook series includes key contributions presented by different researchers These contributions represent a wide coverage of the state of the art and the emerging research directions in intelligent transportation vehicles A cura dell editore

Machine Learning-based Natural Scene Recognition for Mobile Robot Localization in An Unknown Environment Xiaochun Wang,Xiali Wang,Don Mitchell

Wilkes,2019-08-12 This book advances research on mobile robot localization in unknown environments by focusing on machine learning based natural scene recognition The respective chapters highlight the latest developments in vision based machine perception and machine learning research for localization applications and cover such topics as image segmentation based visual perceptual grouping for the efficient identification of objects composing unknown environments classification based rapid object recognition for the semantic analysis of natural scenes in unknown environments the present understanding of the Prefrontal Cortex working memory mechanism and its biological processes for human like localization and the application of this present understanding to improve mobile robot localization The book also features a perspective on bridging the gap between feature representations and decision making using reinforcement learning laying the groundwork for future advances in mobile robot navigation research *Design, Modeling and Experiments of 3-DOF Electromagnetic Spherical Actuators* Liang Yan,I-Ming Chen,Chee Kian Lim,Guilin Yang,Kok-Meng Lee,2011-06-06 A spherical actuator is a novel electric device that can achieve 2 3 DOF rotational motions in a single joint with electric power input It has advantages such as compact structure low mass moment of inertia fast response and non singularities within the workspace It has promising applications in robotics automobile manufacturing medicine and aerospace industry This is the first monograph that introduces the research on spherical actuators systematically It broadens the scope of actuators from conventional single axis to multi axis which will help both beginners and researchers to enhance their knowledge on electromagnetic actuators Generic analytic modeling methods for magnetic field and torque output are developed which can be applied to the development of other electromagnetic actuators A parametric design methodology that allows fast analysis and design of spherical actuators for various applications is proposed A novel non contact high precision 3 DOF spherical motion sensing methodology is developed and evaluated with experiments which shows that it can achieve one order of magnitude higher precision than conventional methods The technologies of nondimensionalization and normalization are introduced into magnetic field analysis the first time and a benchmark database is established for the reference of other researches on spherical actuators **Advances in Engineering Design** Anamika Prasad,Shakti S. Gupta,R. K. Tyagi,2019-04-27 This book presents select proceedings of the International Conference on Future Learning Aspects of Mechanical Engineering FLAME 2018 The book covers mechanical design areas such as computational mechanics finite element modeling computer aided designing tribology fracture mechanics and vibration The book brings together different aspects of engineering design and will be useful for researchers and professionals working in this field *Innovations and Advances in Computing, Informatics, Systems Sciences, Networking and Engineering* Tarek Sobh,Khaled Elleithy,2014-11-07 Innovations and Advances in Computing Informatics Systems Sciences Networking and Engineering This book includes a set of rigorously reviewed world class manuscripts addressing and detailing state of the art research projects in the areas of Computer Science Informatics and Systems Sciences and Engineering It includes selected papers from the conference

proceedings of the Eighth and some selected papers of the Ninth International Joint Conferences on Computer Information and Systems Sciences and Engineering CISSE 2012 Includes chapters in the most advanced areas of Computing Informatics Systems Sciences and Engineering Accessible to a wide range of readership including professors researchers practitioners and students

Fusion of Hard and Soft Control Strategies for the Robotic Hand Cheng-Hung Chen, Desineni Subbaram Naidu, 2017-10-09 An in depth review of hybrid control techniques for smart prosthetic hand technology by two of the world's pioneering experts in the field Long considered the stuff of science fiction a prosthetic hand capable of fully replicating all of that appendage's various functions is closer to becoming reality than ever before This book provides a comprehensive report on exciting recent developments in hybrid control techniques one of the most crucial hurdles to be overcome in creating smart prosthetic hands Coauthored by two of the world's foremost pioneering experts in the field Fusion of Hard and Soft Control Strategies for Robotic Hand treats robotic hands for multiple applications It begins with an overview of advances in main control techniques that have been made over the past decade before addressing the military context for affordable robotic hand technology with tactile and or proprioceptive feedback for hand amputees Kinematics homogeneous transformations inverse and differential kinematics trajectory planning and dynamic models of two link thumb and three link index finger are discussed in detail The remainder of the book is devoted to the most promising soft computing techniques particle swarm optimization techniques and strategies combining hard and soft controls In addition the book Includes a report on exciting new developments in prosthetic robotic hand technology with an emphasis on the fusion of hard and soft control strategies Covers both prosthetic and non prosthetic hand designs for everything from routine human operations robotic surgery and repair and maintenance to hazardous materials handling space applications explosives disposal and more Provides a comprehensive overview of five fingered robotic hand technology kinematics dynamics and control Features detailed coverage of important recent developments in neuroprosthetics Fusion of Hard and Soft Control Strategies for Robotic Hand is a must read for researchers in control engineering robotic engineering biomedical sciences and engineering and rehabilitation engineering

Algorithmic Foundations of Robotics VI Michael Erdmann, David Hsu, Mark Overmars, A. Frank van der Stappen, 2005-06-23 Robot algorithms are abstractions of computational processes that control or reason about motion and perception in the physical world Because actions in the physical world are subject to physical laws and geometric constraints the design and analysis of robot algorithms raise a unique combination of questions in control theory computational and differential geometry and computer science Algorithms serve as a unifying theme in the multi disciplinary field of robotics This volume consists of selected contributions to the sixth Workshop on the Algorithmic Foundations of Robotics This is a highly competitive meeting of experts in the field of algorithmic issues related to robotics and automation

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