

ETHz Robotics and MLSS summer schools' review

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Outline

ETHz Robotics summer school

ETH Zurich

Symposium

Summer school

Machine Learning Summer School

Organization

Lectures



ETH Zurich

- ▶ ETH Zurich (Swiss Federal Institute of Technology in Zurich)
- ▶ As of August 2018, 32 Nobel laureates, 4 Fields Medalists, and 1 Turing Award winner have been affiliated with the Institute, including **Albert Einstein**.
- ▶ Ranked **6th** in the world according to QS World University Ranking, and **10th** in the world according to Times Higher Education World Rankings.

Organization

- ▶ Robotics Systems Lab (Marco Hutter h-index 29)
- ▶ Autonomous Systems Lab (Roland Siegwart h-index 97)
- ▶ Vision for Robotics Lab (Margarita Chli h-index 21)

Overview

- ▶ Symposium: 27-28 June 2019
- ▶ Summer School Dates: 29 June - 1 July 2019
- ▶ Swiss Search and Rescue Robotics Week (ARCHE): 01-05 July 2019



Program

	ETH Robotics Symposium		Summer School			ARCHE			
	Th 27 June	Fr 28 June	Sa 29 June	Su 30 June	Mo 01 July	Tu 02 July	We 03 July	Th 04 July	Fr 05 July
8:00									
8:30									
9:00		Invited Talks	Lecture	Lecture	Lecture	Special events by professional organizations (e.g. firefighters, redog, ABC, ...)			
9:30									
10:00			Tutorial	Tutorial	Tutorial				
10:30									
11:00									
11:30	Lunch		Coffee	Coffee	Coffee				
12:00		Lunch	Lecture	Lecture	Trials				
12:30									
13:00	Lunch		Lunch	Lunch					
13:30									
14:00	Invited Talks		Bus transfer to Wangen / check-in Training Facility / Introduction to Facilities	Tutorial	Tutorial	Trials			
14:30									
15:00									
15:30		Coffee		Coffee	Coffee				
16:00		Trials		Trials					
16:30				Summer School Robotic Challenge					
17:00	Lab Tours	Introduction Summer School / Challenge description / Introduction to Robotic Platforms							
17:30									
18:00									
18:30	Symposium Evening event								
19:00									
19:30									
20:00									
20:30			Free Time	Social Activity	Social Event BBQ				

Day 1

- ▶ Sanjiv Singh - Why drive autonomously when you can fly autonomously?
(CMU - Near Earth Autonomy)
- ▶ Achim Walter - Agriculture and robotics: A joyful marriage?
(ETH Zurich)
- ▶ Marc Pollefeys - Mixed reality and robotics
(ETH Zurich and Microsoft)
- ▶ Dieter Fox - Toward robust manipulation in complex scenes
(Nvidia)
- ▶ Jamie Paik - Reconfigurable robots for interactive intuitive interfaces
(EPFL)

Day 2

- ▶ Seth Hutchinson - Design, Modeling and Control of a Biologically-Inspired Bat Robot (Georgia Tech)
- ▶ Yulia Sandamirskaya - The neuromorphic computing and sensing technology in robotics (INI-UZH)
- ▶ Andrea Censi - Liability, ethics, and culture-aware behavior specification using rulebooks (ETH Zurich and nuTonomy / Aptiv)
- ▶ Sami Haddadin - The gentle robot (TU Munich and Franka Emika)

Work to follow



Figure 2

Work to follow



INGREDIENTS OF A BASIC MANIPULATION SYSTEM

- **Task and motion planning**
 - Determine sequence of high-level commands and collision-free trajectories to achieve target configuration
- **State estimation and perception**
 - Infer relevant quantities from sensor data (objects, drawers, doors, manipulator, contacts, ...)
- **Object grasping and placement**
 - Determine good grasps for objects given constraints (gripper, local geometry, placement)
- **Trajectory generation and control**
 - Real-time, reactive generation of control commands to safely move robot / gripper toward goals

Figure 3

Work to follow

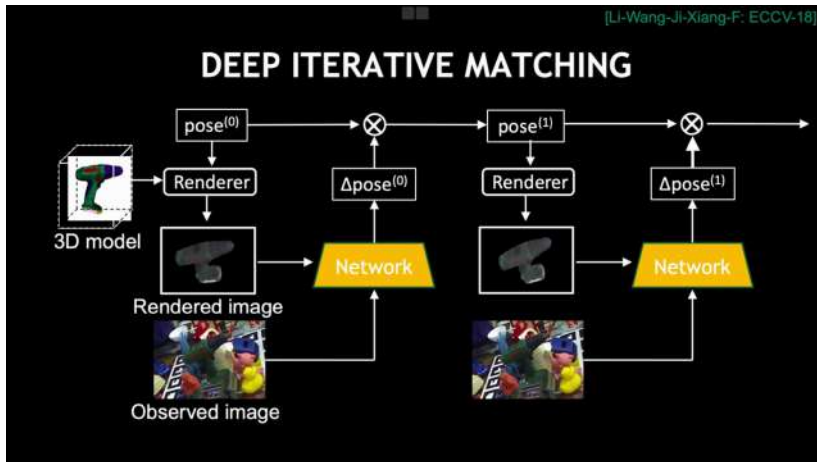


Figure 4

Work to follow

[Eppner-Mousavian-F: under review]

LEARNING TO GRASP UNKNOWN OBJECTS

NVIDIA Flex/PhysX Sim to Assess Grasp Quality



- Generate for 1,000s of objects with 1,000s of grasps each
- Learn to pickup unknown objects, choose accessible grasps in clutter, ...

25 NVIDIA

Figure 5

Work to follow

6DOF-GRASPNET: LEARNING TO GRASP UNKNOWN OBJECTS

[Mousavian-Eppner-F: arXiv:1905.10520]

- **Grasp sampler:** Variational Auto-Encoder learns to sample variety of successful 6D grasps from 3D point clouds
- **Grasp evaluator:** Provides quality measure of object and sampled grasp (pointcloud)
- **Grasp refinement:** Use gradient of evaluator network to improve grasp

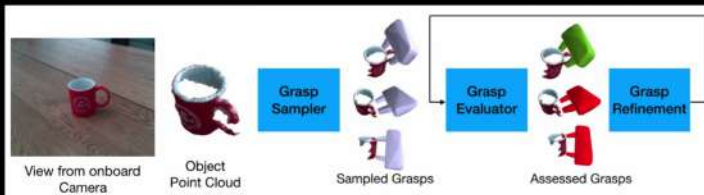


Figure 6

Work to follow

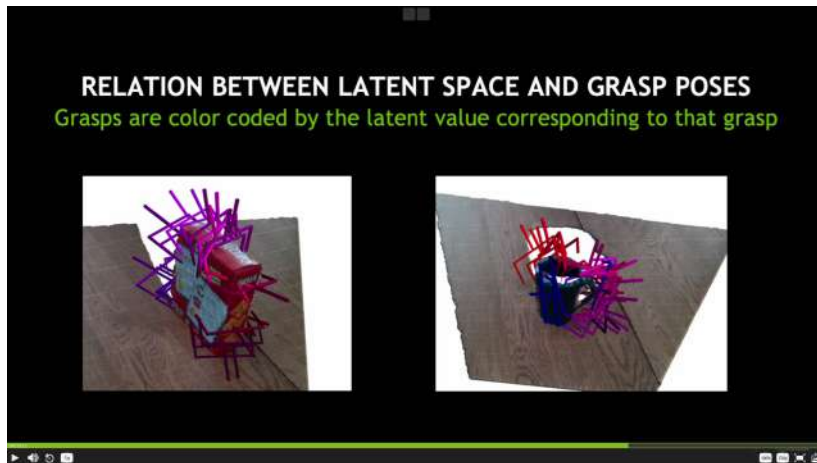


Figure 7

Work to follow

The gentle robot.

SAMI HADDADIN



Figure 8

Work to follow

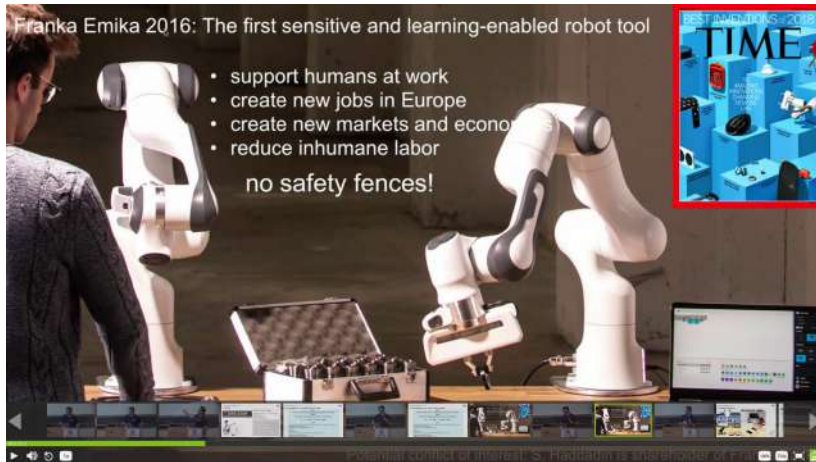


Figure 9

Work to follow

Munich School of Robotics and Machine Intelligence
 Technische Universität München



Skill framework I

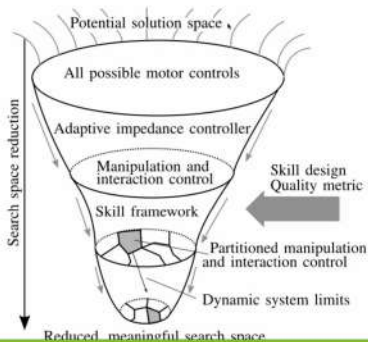


Figure 10

Work to follow

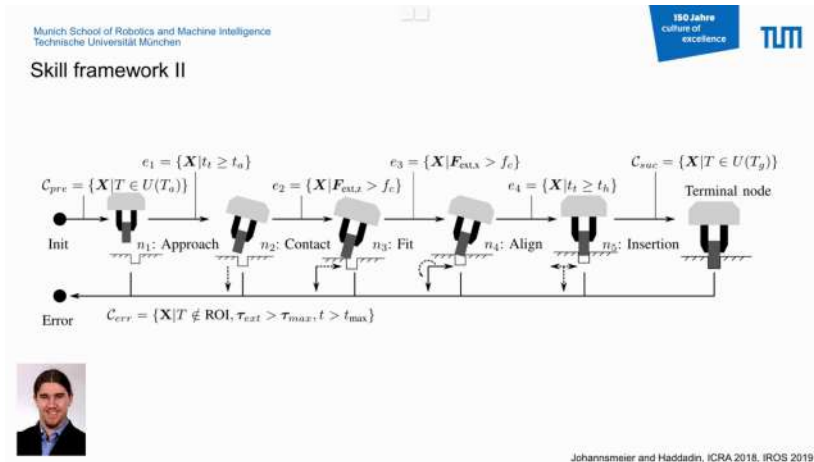


Figure 11

Work to follow

Munich School of Robotics and Machine Intelligence
 Technische Universität München



Skill framework II

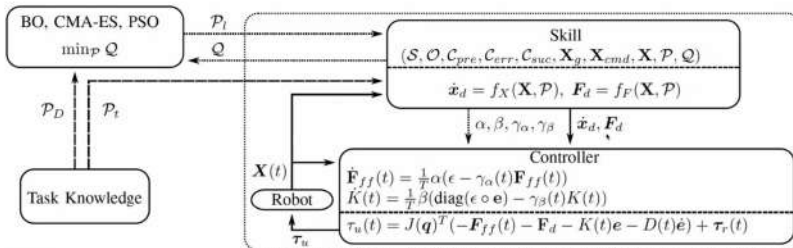
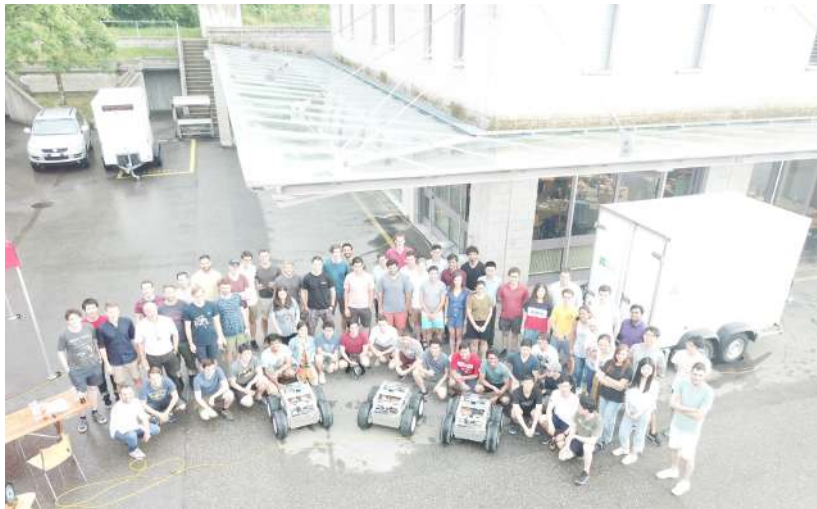


Figure 12

Summer school



My team



Figure 14

Lectures and tutorials

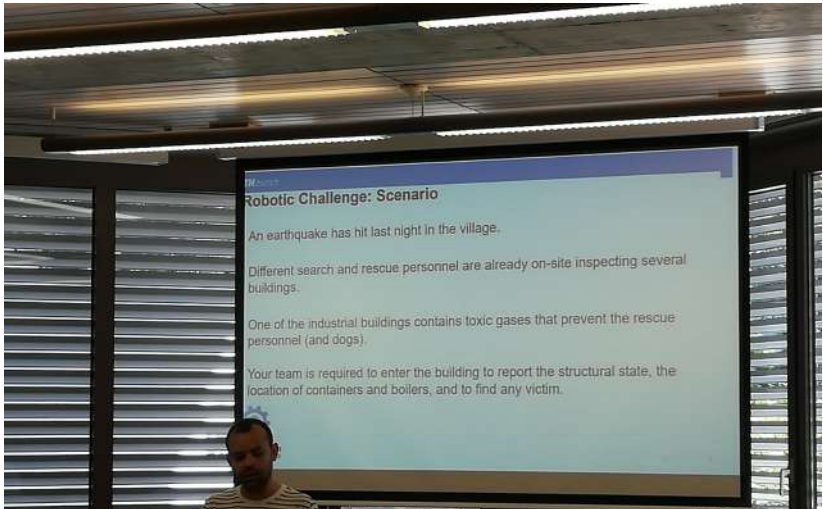
1. Robot Introduction (platform and connection to the robot)
2. State estimation (Calibration and batch optimization, Online sensor fusion, Latency compensation)
3. Robot motion planning (Graph search methods e.g. A^* , Collision avoidance, Sampling-based planning)
4. Trajectory optimization or optimization-based control (Policy search, Trajectory optimization, Dynamic programming, Model Predictive Control)
5. Teaching Robots to See: SLAM and beyond (FAST, BRIEF, BRISK, Filtering, CVI-SLAM)

Robot



Figure 15

Robotics challenge



Robotics challenge



Organization

- ▶ Marc Deisenroth (Imperial College London) h-index 30
- ▶ Arthur Gretton (University College London) h-index 52

Program

[illegible]

Figure 18

Lectures

- ▶ Shakir Mohamed (DeepMind): Variational Inference
- ▶ John Duchi (Stanford University): Optimization
- ▶ Kevin Webster (FeedForward, Imperial College London): Deep Learning
- ▶ Pierre Richemond (Imperial College London): Deep Learning
- ▶ Kai Arulkumaran (Imperial College London): Deep Learning

Lectures

- ▶ Katja Hofmann (Microsoft Research Cambridge): Reinforcement Learning
- ▶ Sanmi Koyejo (University of Illinois at Urbana-Champaign; Google AI Accra): Interpretability
- ▶ James Hensman (PROWLER.io): Gaussian Processes
- ▶ Moustapha Cissé (AIMS Rwanda and Google AI, Accra): AI for Good
- ▶ Julien Cornebise (Element AI): AI for Good

Lectures

- ▶ Lorenzo Rosasco (IIT, University of Genova, MIT): Kernels
- ▶ Michael Betancourt (Symplectomorphic): Markov Chain Monte Carlo
- ▶ Sarah Filippi (Imperial College London): Approximate Bayesian Computation
- ▶ Timnit Gebru (Google): Fairness in Machine Learning

Lectures

- ▶ Karen Livescu (Toyota Technological Institute at Chicago): Speech Processing
- ▶ Samory Kpotufe (Columbia University): Learning Theory
- ▶ Barbara Engelhardt (Princeton University): Machine Learning in Computational Biology
- ▶ Stefanie Jegelka (MIT): Submodularity

MLSS



Figure 19

My group at MLSS



Figure 20

Work to follow

1. MPC with Gaussian Processes (Prof. Melanie Zeilinger - ETH)

Thanks!