Reversing the reality gap

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1 Introduction

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> The overarching goal of our lab is to develop novel methods for search and exploration. Specifically, we are interested in developing robot learning methods that enable robots to navigate any terrain. To construct devices that operate in rough, unstructured environments we design them with multiple modes of locomotion (e.g., wheeled, flight, walking, etc.). We refer to such robots as adaptive-locomotion robots; they are able to dynamically choose different methods of locomotion at runtime (see Figure 1 for an example). An example application for such a device is aiding first responders looking for victims of a tornado, such as the one that affected our neighboring community (Joplin, Missouri) in 2011.

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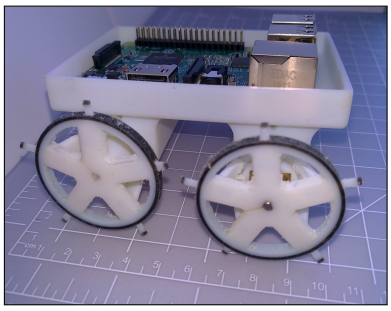

(a) Robot Prototype

(b) Application

(c) Environment

Figure 1: (a) Our adaptive-locomotion robot. (b) An example mobile application showing a user-traced path. (c) An area that we would like to search with a semi-autonomous mobile robot.

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References

[1] A. Einstein, "Zur Elektrodynamik bewegter Körper. (German) [On the electrodynamics of moving bodies]," *Annalen der Physik*, vol. 322, no. 10, pp. 891–921, 1905. DOI: http://dx.doi.org/10.1002/andp.19053221004.

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