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This talk will describe methods that exploit experience to solve motion planning and optimal control problems much faster than de novo methods. September 25, , Columbia University How to Make, Sense, and Make Sense of Contact in Robotic Manipulation - intermitent audio for the first ~20mins Dexterous manipulation is a key open problem for many new robotic applications, owing in great measure to the difficulty of dealing with transient contact.

dblp: Martha E. Pollack

He has worked in robotic perception since the first DARPA grand challenge and his group focuses on enabling robots to better see and understand their environment. She holds both an M.

dblp: Martha E. Pollack

Robotics and Autonomous Systems, Special Issue Semantic Knowledge in Robotics 56 11 :875-877, 2008. May 2, , Northeastern University Robotic Manipulation Without Geometric Models Most approaches to planning for robotic manipulation take a geometric description of the world and the objects in it as input. She received an NSF CAREER award in 2010, a DARPA Young Faculty Award in 2012 and the Fiona Ip Li '78

and Donald Li '75 Excellence in teaching award in 2013.

Joachim Hertzberg's Publications

He was an editor of the IEEE Transactions on Robotics, program co-chair of the 2008 AAAI Conference on Artificial Intelligence, and program chair of the 2013 Robotics: Science and Systems conference.

Chair for Dynamics/Mechatronics

I show how implicit communication of topological group plans achieves rapid convergence to a group consensus, and how a robot in the group can deliberately influence the ultimate outcome to maximize joint performance, yielding pedestrian comfort with the robot.

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