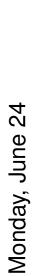
General Schedule



	Monday	Tuesday	Wednesday	Thursday	Friday
08:00	08:45 Welcome				
09:00	09:00 Alyosha Ephros ^{55 min} H 0104	09:00 Rodney Brooks 55 min H 0104	09:00 Julia Parrish 55 min H 0104	09:00 Workshops 1-14	09:00 Workshops 14-24
10:00	09:55 Short Talks 35 min H 0104 10:30 Break	09:55 Short Talks 35 min H 0104 10:30 Break	09:55 Short Talks 35 min H 0104 10:30 Break	90 min MAR 10:30 Break	90 min MAR 10:30 Break
11:00	30 min Lichthof 11:00 Talks 1 long + 5 short H 0104 60 min H 0104	30 min Lichthof 11:00 Talks 1 long + 5 short 60 min H 0104	11:00 Talks 1 long + 5 short H 0104	11:00 Workshops 1-14	11:00 Workshops 14-24
12:00	12:00 Lunch Break	12:00 Lunch Break	12:00 Lunch Break	90 min MAR	90 min MAR
13:00	90 min	90 min	90 min	12:30 Lunch Break Lab Tour	12:30 Lunch Break
10.00	13:30 Raffaello D'Andrea 55 min H 0104	13:30 Talks	13:30 Neil Burgess ^{55 min} H 0104	90 min MAR 14:00	90 min MAR
14:00	14:25 Short Talks 35 min H 0104	2 long + 6 short H 0104	14:25 Short Talks 35 min H 0104	Workshops 1-14	Workshops 14-24
15:00	15:00 Break 30 min Lichthof 15:30 Spotlight	15:00 Break 30 min Lichthof 15:30	15:00 Break 25 min Lichthof 15:30 Open Forum	90 min MAR 15:30 Break	90 min MAR 15:30 Break
16:00	16:00 Short Talks 30 min H 0104 16:30 Spotlight 30 min H 0104	Interactive Presentation	45 min H 0104 16:00 Interactive	16:00 Workshops 1-14	16:00 Workshops 14-24
17:00	17:00 Opening Interactive		Presentation	90 min MAR	90 min MAR
18:00	Presentation	2.5 h Lichthof	18:00 Closing 30 min H 0104		
10:00	Interactive Food at 19:00		Interactive Presentation cont'd		
19:00		20:00	Interactive Food at 18:30		
20:00		Banquet	4.5 h Lichthof		
21:00	5 h Lichthof	2 h at Kater Holzig			





08:45 is Welcome 09:00 4s.10 invited Time. Her Majesty the Data 10:00 4s.10 invited Time. Her Majesty the Data 10:00 2s.20 Colfee Break 10:00 2s.20 Colfee Break 11:00 2s.20 Colfee Break 12:00 2s.20 Colfee Break 13:00 2s.20 Colfee Break 14:00 2s.20 Colfee Break 15:00 2s.20 Colfee Break	Start	Length		Interactive session ID	Sion ID
99.10 Invited Talk: Her Majesty the Data 5 poil: Multi-Hypothesis Social Grouping and Tracking for Mobile Robotis 5 poil: Multi-Hypothesis Social Grouping and Tracking for Mobile Robotis 5 poil: Audit-Hypothesis Social Grouping and Tracking for Mobile Robotis 5 poil: Audit-Hypothesis Social Grouping and Tracking for Mobile Robotis 5 poil: High Altitude Stereo Visual Odomeiry 5 pot4: Learning Somantic Maps from Natural Language Descriptions 5 pot9: Toward Interactive Grounded Language Acquisition 30 Coffee Break 2045 pot6: Anticipating Human Activities using Object Affordances for Reactive Robotic Response 5 pot9: Online Coverage by a Tethered Autonomous Mobile Robot in Planar Unknown Environments 5 pot9: Online Coverage by a Tethered Autonomous Mobile Roboti Planaria 5 pot9: Metastability for High-Dimensional Walking Systems on Stochastically Networked Underwater Vehicles with 7 pot9: A Teach Decentralized Cooperative Raylaginon Algorithm for Acoustically Networked Underwater Vehicles with 8 pot9: Metastability for High-Dimensional Walking Systems on Stochastically Networked Underwater Vehicles with 8 pot9: Metastability for High-Dimensional Walking Systems on Stochastically Networked Underwater Vehicles with 8 pot9: Capusing Robotic Compensional Malking Systems on Stochastical Manipulation of Payloads Suspended by Cables from Multiple Quadrotor Robots 9 pt1: Dynamics Control in Dynamic Environments from Temporal Logic Specifications 5 pt1: The Influence of Motion Path and Assembly Sequence on Stability of Assemblies 5 pt1: The Influence of Motion Path and Assembly Sequence on Stability of Assemblies 9 pt2: Minimum Constraint Displacement Motion Planning 9 pt2: Minimum Constraint Displacement Motion Planning 9 pt3: Active Bayesian Perception and Planning in the Confinuous Space: A POMDP Approach 5 pt3: Active Bayesian Perception and Planning in the Confinuous Space: A POMDP Approach 5 pt3: Active Bayesian Perception and Planning in the Confinuous Space: A POMDP Approach 5 pt3: Active Bayesian Perception and Pla	08:45	15			
5 p01: Multi-Hypothesis Social Grouping and Tracking for Mobile Robots 5 p02: Audio based Relative Positioning System for a Swarm of Micro Air Vehicles 5 p02: Audio based Relative Positioning System for a Swarm of Micro Air Vehicles 5 p03: High Altitude Stereo Visual Odometry 5 p04: Learning Semantic Mass from Natural Language Descriptions 6 p03: Toward Interactive Grounded Language Acquisition 7 Coffee Break 20-5 p06: Anticipating Human Activities using Object Africdances for Reactive Robotic Response 7 p07: Online Ocoarga by a Tehhered Autonomous Mobile Robot in Planar Unknown Environments 5 p08: Quantitative Exquation of Standing Stabilization Using Stiff and Complical Actuators 5 p08: Anticipating Human Activities using Object Africdances for Reactive Robotic Manipulation of Standing Stabilization Using Stiff and Complicat Actuators 5 p08: Malesatability for High-Dimensional Waking Systems on Stochastically Robot Human 7 p10: An Exact Decentralized Cooperative Navigation Algorithm for Acoustically Networked Underwater Vehicles with Robustness to Faulty Communication: Theory and Experiment 5 p10: An Exact Decentralized Cooperative Navigation Algorithm for Acoustically Networked Underwater Vehicles with Robustness to Faulty Communication: Theory and Experiment 6 p11: Dynamics. Control and Planning for Cooperative Manipulation of Payloads Suspended by Cables from Multiple Ouadrotor Robots 7 p18: Receding Plorizon Control in Dynamic Environments from Temporal Logic Specifications 5 p13: Receding Plorizon Control in Dynamic Environments from Temporal Logic Specifications 5 p13: Receding Multiplation as Trajectory Optimization 5 p13: The Influence of Motion Path and Assembly Sequence on Stability of Assemblies 7 p16: The Influence of Motion Path and Assembly Sequence on Stability of Assemblies 8 p17: Minimum Constraint Displacement Motion Planning 8 p17: Animum Constraint Displacement Motion Planning 9 p18: Active Bayesian Perception and Planning in the Continuous Space: A PoWDP Approach 9 p18: Integrated Percept	00:60	45+10		Alyosha Ephros	
5 p02: Audio based Relative Positioning System for a Swarm of Micro Air Vehicles 5 p03: High Airlude Stereo Visual Odometry 5 p04: Learning Semantic Maps from Natural Language Descriptions 5 p04: Learning Semantic Maps from Natural Language Descriptions 30 Coffee Break 20+5 p06: Toward Interactive Grounded Language Acquisition 30 Coffee Break 20+5 p06: Anticipating Human Activities using Object Affordances for Reactive Robotic Response 5 p07: Online Coverage by a Tethered Autonomous Mobile Robot in Planar Unknown Environments 5 p08: Quantitative Evaluation of Standing Systems on Sborbastically Rough Terrain 5 p10: An Exact Decentratived Cooperative Malayland systems on Sborbastically Rough Terrain 5 p10: An Exact Decentrative Acquisition Algorithm for Acoustically Networked Underwater Vehicles with Robustness to Faulty Communication: Theory and Experiment 5 p11: Dynamics, Control and Planning for Cooperative Manipulation of Payloads Suspended by Cables from Multiple 0 Lunch Break 45+10 Invited Talk: Actuated Wingsults for Unconstrained Human Flight 5 p12: Deep Learning for Detecting Robotic Grasps 90 Lunch Break 45+10 Invited Talk: Actuated Wingsults for Unconstrained Environments from Temporal Logic Specifications 91 p13: Receding Horizon Control in Dynamic Environments from Temporal Logic Specifications 91 p13: Receding Horizon Control in Dynamic Environments Roboti Interaction 91 p15: Pregrasp Manipulation as Trajectory Optimization 91 p15: Pregrasp Manipulation as Trajectory Optimization 91 p16: The Influence of Motion Path and Assembly Sequence on Stability of Assemblies 91 p19: Active Bayesian Perception and Planning in the Confinuous Space: A POMDP Approach 91 p19: Active Bayesian Perception and Planning in the Confinuous Space: A POMDP Approach 91 p19: Active Bayesian Perception for Simultaneous Object Localization and Identification 92 p20: Caussian Process-Based Decentralized Data Fusion and Active Sensing for Mobility-on-Demand System 93 Early Career Spotlight: High-Level Verifiable Robotics 94 Find	09:55	2		Matthias Luber, Kai Arras	10
5 p03: High Altitude Stereo Visual Odometry 5 p04: Learning Semantic Maps from Natural Language Descriptions 5 p04: Learning Semantic Maps from Natural Language Acquisition 30 Coffee Break 20+5 p06: Anticipating Human Activities using Object Aftordances for Reactive Robotic Response 5 p07: Online Coverage by a Tehtreed Autonomous Mobile Robot in Planar Unknown Environments 5 p08: Metastability for High-Dimensional Walking Systems on Stochastically Rough Terrain 5 p10: An Exact Decentralized Cooperative Manipulation of Stochastically Rough Terrain 5 p10: An Exact Decentralized Cooperative Manipulation of Payloads Suspended by Cables from Multiple 9 Lunch Break 45+10 Invited Talk: Actuated Wingsults for Unconstrained Human Flight 5 p11: Operation Control in Dynamic Environments from Temporal Logic Specifications 5 p14: On Provably Safe Obstacle Wondance for Autonomous Robotic Ground Vehicles 5 p14: The Influence of Motion Path and Assembly Sequence on Stability of Assemblies 5 p16: The Influence of Motion Path and Assembly Sequence on Stability of Assemblies 5 p16: The Influence of Motion Path and Assembly Sequence on Stability of Assemblies 5 p17: Minimum Constraint Displacement Motion Planning in the Continuous Space: A POMDP Approach 5 p18: Integrated Perception and Planning in the Continuous Space: A POMDP Approach 5 p18: Integrated Perception Proving Integrated Data Fusion and Active Sensing for Mobility-on-Demand System 5 p19: Career Spotlight: High-Level Verifiable Robotics 6 p19: Active Bayesian Process-Based Decentralized Data Fusion and Active Sensing for Mobility-on-Demand System 7 Department Session and Interactive Food 6 End Oseases Spaces Active Procession and Session		2		Meysam Basiri, et al.	02
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5 p08: Quantitative Evaluation of Standing Stabilization Using Stiff and Compliant Actuators 5 p09: Metastability for High-Dimensional Walking Systems on Stochastically Rough Terrain 5 p10: An Exat Decentralized Cooperative Navigation Algorithm for Acoustically Networked Underwater Vehicles with Rebustness to Paulty Communication: Theory and Experiment 5 p11: Dynamics, Control and Planning for Cooperative Manipulation of Payloads Suspended by Cables from Multiple Quadrofor Robots 90 Lunch Break 45-10 Invited Talk: Actuated Wingsuits for Unconstrained Human Flight 5 p12: Deep Learning for Detecting Robotic Grasps 5 p13: Receding Horizon Control in Dynamic Environments from Temporal Logic Specifications 5 p14: On Provably Safe Obstacle Avoidance for Autonomous Robotic Ground Vehicles 5 p15: Pregrasp Manipulation as Trajectory Optimization 5 p16: The Influence of Motion Path and Assembly Sequence on Stability of Assemblies 90 Coffee Break 91 Early Career Spotlight: The Mathematics of Human Robot Interaction 91 T: Minimum Constraint Displacement Motion Planning 91 P17: Minimum Constraint Displacement Motion Planning 91 P18: Integrated Perception and Planning in the Continuous Space: A POMDP Approach 91 P20: Gaussian Perception for Simultaneous Object Localization and Identification 91 Early Career Spotlight: High-Level Verifiable Robotics 92 Deening Session and Interactive Prode 94 Depening Session and Interactive Prode 95 End of session	11:25	2		lddo Shnaps, Elon Rimon	07
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5 pt1: Dynamics, Control and Planning for Cooperative Manipulation of Payloads Suspended by Cables from Multiple Quadrotor Robots 30 Lunch Break 45+10 Invited Talk: Actuated Wingsuits for Unconstrained Human Flight 5 pt2: Deep Learning for Detecting Robotic Grasps 5 pt3: Receding Horizon Control in Dynamic Environments from Temporal Logic Specifications 5 pt4: On Provably Safe Obstacle Avoidance for Autonomous Robotic Ground Vehicles 5 pt3: Receding Horizon Control in Dynamic Environments from Temporal Logic Specifications 5 pt4: On Provably Safe Obstacle Avoidance for Autonomous Robotic Ground Vehicles 5 pt6: The Influence of Motion Path and Assembly Sequence on Stability of Assemblies 30 Coffee Break 30 Early Career Spotlight: The Mathematics of Human Robot Interaction 5 pt7: Minimum Constraint Displacement Motion Planning 5 pt8: Integrated Perception and Planning in the Continuous Space: A POMDP Approach 5 pt8: Integrated Perception and Planning in the Continuous Space: A POMDP Approach 5 pt9: Active Bayesian Perception for Simultaneous Object Localization and Identification 5 pt20: Gaussian Process-Based Decentralized Data Fusion and Active Sensing for Mobility-on-Demand System 30 Early Career Spotlight: High-Level Verifiable Robotics 5 h Opening Session and Interactive Proof End of session End of session		S)		Jeffrey Walls, Ryan Eustice	10
90 Lunch Break 45+10 Invited Talk: Actuated Wingsuits for Unconstrained Human Flight 5 pt12: Deep Learning for Detecting Robotic Grasps 5 pt12: Deep Learning for Detecting Robotic Grasps 5 pt13: Receding Horizon Control in Dynamic Environments from Temporal Logic Specifications 5 pt13: No Provably Safe Obstacle Avoidance for Autonomous Robotic Ground Vehicles 5 pt13: Pregrasp Manipulation as Trajectory Optimization 5 pt15: Pregrasp Manipulation as Trajectory Optimization 5 pt16: The Influence of Motion Path and Assembly Sequence on Stability of Assemblies 30 Coffee Break 30 Early Career Spotlight: The Mathematics of Human Robot Interaction 5 pt17: Minimum Constraint Displacement Motion Planning 5 pt18: Integrated Perception and Planning in the Continuous Space: A POMDP Approach 5 pt19: Active Bayesian Perception for Simultaneous Object Localization and Identification 5 pt20: Gaussian Process-Based Decentralized Data Fusion and Active Sensing for Mobility-on-Demand System 30 Early Career Spotlight: High-Level Verifiable Robotics 5 h Opening Session and Interactive Presentation of today's talks Interactive Food End of session		5		Koushil Sreenath, Vijay Kumar	Ξ
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5 p16: The Influence of Motion Path and Assembly Sequence on Stability of Assemblies 30 Coffee Break 30 Early Career Spotlight: The Mathematics of Human Robot Interaction 5 p17: Minimum Constraint Displacement Motion Planning 5 p18: Integrated Perception and Planning in the Continuous Space: A POMDP Approach 5 p19: Active Bayesian Perception for Simultaneous Object Localization and Identification 5 p20: Gaussian Process-Based Decentralized Data Fusion and Active Sensing for Mobility-on-Demand System 30 Early Career Spotlight: High-Level Verifiable Robotics 5 h Opening Session and Interactive Presentation of today's talks Interactive Food End of session		2		Jennifer King, et al.	15
30 Coffee Break 30 Early Career Spotlight: The Mathematics of Human Robot Interaction 5 p17: Minimum Constraint Displacement Motion Planning 5 p17: Minimum Constraint Displacement Motion Planning 5 p18: Integrated Perception and Planning in the Continuous Space: A POMDP Approach 5 p19: Active Bayesian Perception for Simultaneous Object Localization and Identification 5 p20: Gaussian Process-Based Decentralized Data Fusion and Active Sensing for Mobility-on-Demand System 30 Early Career Spotlight: High-Level Verifiable Robotics 5 h Opening Session and Interactive Presentation of today's talks Interactive Food End of session		2		Sourav Rakshit, Srinivas Akella	16
 arrly Career Spotlight: The Mathematics of Human Robot Interaction p17: Minimum Constraint Displacement Motion Planning p18: Integrated Perception and Planning in the Continuous Space: A POMDP Approach p19: Active Bayesian Perception for Simultaneous Object Localization and Identification p20: Gaussian Process-Based Decentralized Data Fusion and Active Sensing for Mobility-on-Demand System Early Career Spotlight: High-Level Verifiable Robotics Opening Session and Interactive Presentation of today's talks Interactive Food End of session 	15:00	30			
5 p17: Minimum Constraint Displacement Motion Planning 5 p18: Integrated Perception and Planning in the Continuous Space: A POMDP Approach 5 p19: Active Bayesian Perception for Simultaneous Object Localization and Identification 5 p20: Gaussian Process-Based Decentralized Data Fusion and Active Sensing for Mobility-on-Demand System 30 Early Career Spotlight: High-Level Verifiable Robotics 5 h Opening Session and Interactive Presentation of today's talks Interactive Food End of session	15:30	30		Siddhartha Srinivasa	
5 p18: Integrated Perception and Planning in the Continuous Space: A POMDP Approach 5 p19: Active Bayesian Perception for Simultaneous Object Localization and Identification 5 p20: Gaussian Process-Based Decentralized Data Fusion and Active Sensing for Mobility-on-Demand System 30 Early Career Spotlight: High-Level Verifiable Robotics 5 h Opening Session and Interactive Presentation of today's talks Interactive Food End of session	16:00	2	p17: Minimum Constraint Displacement Motion	Kris Hauser	17
5 p19: Active Bayesian Perception for Simultaneous Object Localization and Identification 5 p20: Gaussian Process-Based Decentralized Data Fusion and Active Sensing for Mobility-on-Demand System 30 Early Career Spotlight: High-Level Veriffable Robotics 5 h Opening Session and Interactive Presentation of today's talks Interactive Food End of session		2		Haoyu Bai, Hsu David, Wee Sun Lee	18
5 p20: Gaussian Process-Based Decentralized Data Fusion and Active Sensing for Mobility-on-Demand System 30 Early Career Spotlight: High-Level Verifiable Robotics 5 h Opening Session and Interactive Presentation of today's talks Interactive Food End of session		ιΩ		Nathan Lepora, Uriel Martinez-Hernandez, Tony Prescott	19
30 Early Career Spotlight: High-Level Verifiable Robotics 5 h Opening Session and Interactive Presentation of today's talks Interactive Food End of session		2		Jie Chen, Kian Hsiang Low and Colin Keng-Yan Tan	20
5 h Opening Session and Interactive Presentation of today's talks Interactive Food End of session	16:30	30		Hadas Kress-Gazit	
Interactive Food End of session	17:00	5 h	Opening Session and Interactive Presentation of	at Lichthof	
	19:00		Interactive Food	at Lichthof	
	22:00		End of session		



Tuesday, June 25

Start	Length		Interactive session ID	Ssion ID
00:60	45+10	Invited Talk: Robotics Research Just Got A Whole Lot More Exciting	Rodney Brooks	
09:55	5	p21: Exploiting Urban Scenes for Vision-aided Inertial Navigation	Dimitrios Kottas, Stergios Roumeliotis	10
	5	p22: Fast Interpolation and Time-Optimization on Implicit Contact Submanifolds	Kris Hauser	02
	2	p23: Sorry Dave, I'm Afraid I Can't Do That: Explaining Unachievable Robot Tasks Using Natural Language	Vasumathi Raman, et al.	03
	5	p24: Generating Legible Motion	Anca Dragan, Siddhartha Srinivasa	04
	5	p25: Bayesian Fusion for Multi-Modal Aerial Images	Alistair Reid, Fabio Ramos	90
10:30	30	Coffee Break		
11:00	20+5	p26: Modeling and Evaluating Narrative Gestures for Humanlike Robots	Chien-Ming Huang, Bilge Mutlu	90
11:25	2	p27: Unsupervised intrinsic calibration of depth sensors via SLAM	Alex Teichman, Stephen Miller, Sebastian Thrun	20
	2	p28: 6-D manipulation with aerial towed-cable systems	Montserra Manubens, Didier Devaurs, Lluis Ros, Juan Cortés	80
	5	p29: Automatic Online Calibration of Cameras and Lasers	Jesse Levinson, Sebastian Thrun	60
	2	p30: Goal Assignment and Trajectory Planning for Large Teams of Aerial Robots	Matthew Turpin, et al.	10
	5	p31: Finding Locally Optimal, Collision-Free Trajectories with Sequential Convex Optimization	John Schulman, et al.	Ξ
12:00	06	Lunch Break		
12:00	06	Robotics in H2020 – latest development: the Robotics Public-Private Partnership and beyond	Room H1036 (next to Lichthof)	
13:30	20+5	p32: Vision-Based State Estimation and Trajectory Control Towards Aggressive Flight with a Quadrotor	Shaojie Shen, et al.	12
13:55	20+5	p33: Optimal Market-based Multi-Robot Task Allocation via Strategic Pricing	Lantao Liu, Dylan Shell	13
14:20	5	p34: Infinite Latent Conditional Random Fields for Modeling Environments through Humans	Yun Jiang, Ashutosh Saxena	4
	5	p35: Real-Time Camera Tracking and 3D Reconstruction Using Signed Distance Functions	Erik Bylow, et al.	15
	5	p36: Grasp Moduli Spaces	Florian T. Pokorny, Kaiyu Hang, Danica Kragic	16
	2	p37: Keyframe-Based Visual-Inertial SLAM using Nonlinear Optimization	Stefan Leutenegger, et al.	17
	5	p38: Maximum Mean Discrepancy Imitation Learning	Beomjoon Kim, Joelle Pineau	18
	5	p39: Perceiving, Learning, and Exploiting Object Affordances for Autonomous Pile Manipulation	Dov Katz, et al.	19
15:00	30	Coffee Break		
15:30	2.5 h	2.5 h Interactive Presentation of today's talks, light snacks and beverages	at Lichthof	
18:00		End of session		
20:00		Banquet	at Kater Holzig	



Wednesday, June 26

Start	Length		Interactive session ID	Sion ID
00:60	45+10	45+10 Invited Talk: Life Lessons: Are Animal Aggregations Appropriate Models for Robotics?	Julia Parrish	
09:55	2	p40: Correct Software Synthesis for Stable Speed-Controlled Robotic Walking	Neil Dantam, et al.	10
	2	p41: Toward a Platform of Human-Like Fingertip Model in Haptic Environment for Studying Sliding Tactile Mechanism	Anh-Van Ho, Shinichi Hirai	02
	2	p42: Incremental Block Cholesky Factorization for Nonlinear Least Squares in Robotics	Lukas Polok	03
	2	p43: Convex Optimization of Nonlinear Feedback Controllers via Occupation Measures	Anirudha Majumdar, et al.	04
	2	p44: Realtime Registration-Based Tracking via Approximate Nearest Neighbour Search	Travis Dick, et al.	90
10:30	30	Coffee Break		
11:00	20+5	p45: A control framework for tactile servoing	Qiang Li, et al.	90
11:25	2	p46: Topological Approach to Using Cables to Separate and Manipulate Sets of Objects	Soonkyum Kim, et al.	07
	2	p47: Learning to Plan for Constrained Manipulation from Demonstrations	Phillips Mike, et al.	08
	2	p48: Incremental Semantically Grounded Learning from Demonstration	Scott Niekum, et al.	60
	2	p49: Fast Scheduling of Multi-Robot Teams with Temporospatial Constraints	Matthew Gombolay, Ronald Wilcox, Julie Shah	10
	5	p50: Adaptive Estimation of Measurement Bias in Three-Dimensional Field Sensors with Angular Rate Sensors: Theory and Comparative Experimental Evaluation	Giancarlo Troni, Louis Whitcomb	Ξ
12:00	06	Lunch Break		
13:30	45+10	45+10 Invited Talk: Neural Mechanisms of Spatial Navigation	Neil Burgess	
14:25	2	p51: Stochastic Motion Planning for Robotic Information Gathering	Geoffrey Hollinger, Gaurav Sukhatme	12
	2	p52: Kinodynamic Planning in the Configuration Space via Velocity Interval Propagation	Quang-Cuong Pham, Yoshihiko Nakamura	13
	2	p53: Approximate Representations for Multi-Robot Control Policies that Maximize Mutual Information	Benjamin Charrow, Vijay Kumar, Nathan Michael	4
	2	p54: Real-Time EMG driven Lower Limb Actuated Orthosis for Assistance As Needed Movement Strategy	Walid Hassani, Samer Mohammed, Yacine Amirat	15
	2	p55: A model of distributional handing interaction for a mobile robot	Chao Shi, et al.	16
15:00	30	Coffee Break		
15:30	45	Open Forum		
16:15	4.5 h	Interactive Presentation of today's talks	at Lichthof	
18:00	30	Best Paper Award and Closing Session	at H 0104	
18:30		Interactive Food	at Lichthof	
21:00		end of main conference		
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Thursday, June 27: Workshops 1-14

□	Room	Title	Chair	Notes
10	4.063	Aerial Mobile Manipulation	R. Voyles	half day/morning
02	0.003	Sensitive Robotics	E. Torres-Jara	half day/morning
03	0.010	Workshop on Common Platforms in Robotic Manipulation	L. Odhner	
40	0.015	4th Workshop on Formal Methods for Robotics and Automation	H. Kress-Gazit	
05	0.016	Inverse Optimal Control & Robot Learning from Demonstration	B. Ziebart	
90	0.007	Robotics Challenges and Vision Workshop	H. Chitsaz	
07	0.002	4th Workshop on RGB-D: Advanced Reasoning with Depth Cameras	A. Saxena	
80	0.001	2nd Workshop on Robots in Clutter: Preparing robots for the real world	M. Zillich	
60	0.011	Active learning in robotics: Exploration, Curiosity, and Interaction	M. Lopes	
10	0.017	From Experience to Concepts and Back	T. Asfour	
11	0.008	Combined Robot Motion Planning and AI Planning for Practical Applications	E. Plaku	
12	4.065	Proposals for experimental protocols for Robotics Research	F. Bonsignorio	half day/afternoon
13	0.009	Robot Design and Control: Advanced Robot Motion	S. Singh	half day/afternoon
4	4.064	Robotic Exploration, Monitoring, and Information Collection: Nonparametric Modeling, Information-based Control, and Planning under Uncertainty	G. Hollinger and S. Karaman	two day
	5.065	Lab Tour: Robotics and Biology Lab, TU Berlin		12:30-13:30



Friday, June 28: Workshops 14-24

Q	Room	Title	Chair	Notes
41	4.064	Robotic Exploration, Monitoring, and Information Collection: Nonparametric Modeling, Information-based Control, and Planning under Uncertainty	G. Hollinger and S. Karaman	two day
15	4.063	Workshop on Multi-View Geometry in Robotics	V. Indelman	half day / morning
16	0.001	Resource-Efficient Integration of Perception, Control and Navigation for Micro Air Vehicles	M. Suppa	
17	0.002	Hierarchical and Structured Learning for Robotics	G. Neumann	
18	0.007	Programming with constraints: Combining high-level action specification and low-level motion execution	G. Borghesan	
19	0.008	Towards Active Lower Limb Prosthetic Systems: Design Issues and Solutions	P. Beckerle	
20	0.010	Robotics for Environmental Monitoring	R. Smith	half day / morning
21	0.011	Manipulation with Uncertain Models	D. Katz	
22	0.016	Human Robot Collaboration	J. Boerkoel	
23	0.017	What did we learn from the simulation phase of the DARPA Robotics Challenge	E. Todorov	
24	4.065	Scientific and Structural Achievements from Academia-Industry Projects in ECHORD	F. Röhrbein half o	half day / afternoon