

Contents

Path Optimization for Nonholonomic Systems: Application to Reactive Obstacle Avoidance and Path Planning	1
<i>Florent Lamiroux, David Bonnafois, Carl Van Geem</i>	
1 Introduction	1
2 Nonholonomic Systems and Path Deformation	3
3 Application to the Mobile Robot Hilare Towing a Trailer	8
4 Application to Path Planning for Trucks and Trailers	12
5 Conclusion and Future Work	16
From Dynamic Programming to RRTs: Algorithmic Design of Feasible Trajectories	19
<i>Steven M. LaValle</i>	
1 Introduction	19
2 Generic Problem Formulation	20
3 Dynamic Programming	22
4 Rapidly-Exploring Random Trees	27
5 Research Challenges	31
Control of Nonprehensile Manipulation	39
<i>Kevin M. Lynch, Todd D. Murphey</i>	
1 Introduction	39
2 Definitions	41
3 Dynamic Underactuated Nonprehensile Manipulation	44
4 Distributed Manipulation and Open Problems	50
Motion Planning and Control Problems for Underactuated Robots	59
<i>Sonia Martínez, Jorge Cortés, Francesco Bullo</i>	
1 Motivating Problems from a Variety of Robotic Applications	59
2 Mathematical Unifying Approach to the Modeling of Robotic Systems	62
3 Existing Results on Planning for Underactuated Systems	65
4 Open Problems and Possible Approaches	69
Motion Description Languages for Multi-Modal Control in Robotics	75
<i>Magnus Egerstedt</i>	
1 Introduction	75
2 Motion Description Languages	76
3 Description Lengths	80
4 A Unified Approach to Control and Hardware Design	84
5 Preliminary Results	86

6 Further Issues	87
Polynomial Design of Dynamics-based Information Processing System	
<i>Masafumi Okada, Yoshihiko Nakamura</i>	
1 Introduction	91
2 Dynamics and Whole Body Motion	92
3 Motion Reduction and Symbolization	93
4 Design of Dynamics-Based Information Processing System	94
5 Generation of the Whole Body Motion	100
6 Conclusion	102
Actuation Methods For Human-Centered Robotics and Associated Control Challenges	
<i>Michael Zinn, Oussama Khatib, Bernard Roth, J. Kenneth Salisbury</i>	
1 Introduction	105
2 New Actuation Approaches	108
3 Conclusion	119
Control of a Flexible Manipulator with Noncollocated Feedback: Time Domain Passivity Approach	
<i>Jee-Hwan Ryu, Dong-Soo Kwon, Blake Hannaford</i>	
1 Introduction	121
2 Review of Time Domain Passivity Approach	122
3 Implementation Issues	127
4 Simulation Examples	129
5 Discussion	130
Cartesian Compliant Control Strategies for Light-Weight, Flexible Joint Robots	
<i>Alin Albu-Schäffer, Gerd Hirzinger</i>	
1 Introduction	135
2 Cartesian Compliant Control	136
3 Control of the flexible joint robot	140
4 Experiments	147
5 Discussion	149
6 Conclusion	149
Toward the Control of Self-Assembling Systems	
<i>Eric Klavins</i>	
1 Introduction	153
2 Related Work	155
3 Modeling	156
4 Discussion	162
5 Conclusion	166

Towards Abstraction and Control for Large Groups of Robots	169
<i>Calin Belta, Vijay Kumar</i>	
1 Introduction	169
2 Definitions and Problem Formulation	171
3 Mean and Covariance Control for Fully Actuated Planar Robots ...	173
4 Mean and Variance Control for Fully Actuated Planar Robots	179
5 Conclusion	182
Omnidirectional Sensing for Robot Control	183
<i>Kostas Daniilidis, Christopher Geyer, Volkan Isler, Ameesh Makadia</i>	
1 Introduction	183
2 A Unifying Projection Model	184
3 The Signal Question	185
4 The Geometry Question	187
5 The Planning Question	191
6 Future Work	196
A Passivity Approach to Vision-based Dynamic Control of Robots with Nonlinear Observer	199
<i>Hiroyuki Kawai, Shintaro Izoë, Masayuki Fujita</i>	
1 Introduction	199
2 Relative Rigid Body Motion	201
3 Visual Feedback System	202
4 Vision-based Robot Control	207
5 Conclusions	212
Visual Servoing along Epipoles	215
<i>Jacopo Piazza, Domenico Prattichizzo, Antonio Vicino</i>	
1 Introduction	215
2 Notation	216
3 Visual Servoing Algorithm	218
4 Experiments	226
5 Conclusions and Open Problems	228
Toward Geometric Visual Servoing	233
<i>Noah John Cowan, Dong Eui Chang</i>	
1 Introduction	233
2 Six DOF Diffeomorphism to Image-space	235
3 Image Jacobian	240
4 Controller	242
5 Conclusion	245

Vision-Based Online Trajectory Generation and Its Application to Catching	249
<i>Akio Namiki, Masatoshi Ishikawa</i>	
1 Introduction	249
2 Related Works	250
3 Vision-Based Online Trajectory Generator	251
4 Experiment	257
5 Conclusion	259
Stability Analysis of Invariant Visual Servoing and Robustness to Parametric Uncertainties	265
<i>Ezio Malis</i>	
1 Introduction	265
2 Modeling	267
3 Vision-based control	269
4 Stability Analysis	270
5 Robustness to Parametric Uncertainties	271
6 Open problems	273
7 Experimental Results	274
8 Conclusion	277