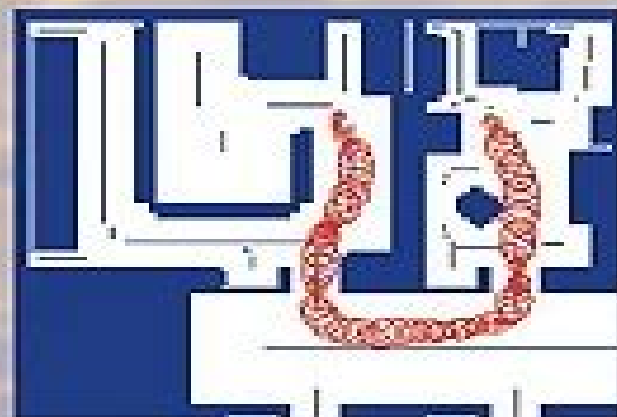


Michael Beetz

LNAI 2554

# Plan-Based Control of Robotic Agents

Improving the Capabilities of  
Autonomous Robots



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# Planbased Control Of Robotic Agents Improving The Capabilities Of Autonomous Robots

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## **Planbased Control Of Robotic Agents Improving The Capabilities Of Autonomous Robots:**

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**Plan-Based Control of Robotic Agents** Michael Beetz, 2014-10-08 Robotic agents such as autonomous office couriers or robot tourguides must be both reliable and efficient. Thus they have to flexibly interleave their tasks, exploit opportunities quickly, plan their course of action, and if necessary, revise their intended activities. This book makes three major contributions to improving the capabilities of robotic agents: first, a plan representation method is introduced which allows for specifying flexible and reliable behavior; second, probabilistic hybrid action models are presented as a realistic causal model for predicting the behavior generated by modern concurrent percept-driven robot plans; third, the system XFRMLEARN, capable of learning structured symbolic navigation plans, is described in detail.

Plan-Based Control of Robotic Agents Michael Beetz, 2003-07-01 Robotic agents such as autonomous office couriers or robot tourguides must be both reliable and efficient. Thus they have to flexibly interleave their tasks, exploit opportunities quickly, plan their course of action, and if necessary, revise their intended activities. This book makes three major contributions to improving the capabilities of robotic agents: first, a plan representation method is introduced which allows for specifying flexible and reliable behavior; second, probabilistic hybrid action models are presented as a realistic causal model for predicting the behavior generated by modern concurrent percept-driven robot plans; third, the system XFRMLEARN, capable of learning structured symbolic navigation plans, is described in detail.

*Agent and Multi-Agent Systems: Technologies and Applications* Adam Grzech, 2007-07-07 This book constitutes the refereed proceedings of the First International Symposium on Agent and Multi-Agent Systems Technologies and Applications KES AMSTA 2007 held in Wroclaw, Poland, in May/June 2007. Coverage includes agent-oriented Web applications, mobility aspects of agent systems, agents for network management, agent approaches to robotic systems, as well as intelligent and secure agents for digital content management.

**Advances in Plan-Based Control of Robotic Agents** Michael Beetz, Leonidas Guibas, Joachim Herztberg, Malik Ghallab, Martha E. Pollack, 2002-11-01 In recent years, autonomous robots including Xavier, Martha 1, Rhino 2, 3, Minerva, and Remote Agent have shown impressive performance in long-term demonstrations. In NASA's Deep Space program, for example, an autonomous spacecraft controller called the Remote Agent 5 has autonomously performed a scientific experiment in space. At Carnegie Mellon University, Xavier 6, another autonomous mobile robot, navigated through an office

vironment for more than a year allowing people to issue navigation commands and monitor their execution via the Internet In 1998 Minerva 7 acted for 13 days as a museum tourguide in the Smithsonian Museum and led several thousand people through an exhibition These autonomous robots have in common that they rely on plan based control in order to achieve better problem solving competence In the plan based approach robots generate control actions by maintaining and executing a plan that is effective and has a high expected utility with respect to the robots current goals and beliefs Plans are robot control programs that a robot can not only execute but also reason about and manipulate 4 Thus a plan based controller is able to manage and adapt the robot's intended course of action the plan while executing it and can thereby better achieve complex and changing tasks Intelligent Autonomous Systems 7 Maria Gini,2002 The goal of the Seventh International Conference on Intelligent Autonomous Systems IAS 7 was to exchange and stimulate research ideas that make future robots and systems more intelligent and autonomous This volume of proceedings contains 71 technical papers by authors from 15 countries

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**Handling Uncertainty and Networked Structure in Robot Control** Lucian Buşoniu,Levente Tamás,2016-02-06 This book focuses on two challenges posed in robot control by the increasing adoption of robots in the everyday human environment uncertainty and networked communication Part I of the book describes learning control to address environmental uncertainty Part II discusses state estimation active sensing and complex scenario perception to tackle sensing uncertainty Part III completes the book with control of networked robots and multi robot teams Each chapter features in depth technical coverage and case studies highlighting the applicability of the techniques with real robots or in simulation Platforms include mobile ground aerial and underwater robots as well as humanoid robots and robot arms Source code and experimental data are available at <http://extras.springer.com> The text gathers contributions from academic and industry experts and offers a valuable resource for researchers or graduate students in robot control and perception It also benefits researchers in related areas such as computer vision nonlinear and learning control and multi agent systems A Stable and Transparent Framework for Adaptive Shared Control of Robots Ribin Balachandran,2024-01-08 Robotic research and developments in computing technologies including artificial intelligence have led to significant improvements in autonomous capabilities of robots Yet human supervision is advisable and in many cases necessary when robots interact with real world outside lab environments This is due to the fact that complete autonomy in robots has not yet been achieved When robots encounter challenges beyond their capabilities a viable solution is to include human operators in the loop who can support robots through teleoperation taking complete control or shared control This monograph focuses on a special form of shared control namely mixed initiative where the final command to the robot is a weighted sum of the commands from the

operator and the autonomous controller The weights fixed or adaptive called authority allocation AA factors decide who has more control authority over the robot Several research groups use different methods to adapt the AA factors online and the benefits of adaptive mixed initiative shared control have been well established in terms of task completion success and operator usability However stability of the overall shared control framework with communication time delays between the operator and the robot is a field that has not been examined extensively This monograph presents methods to improve performance and stability in shared control so that the possibilities of its applications can be widened Firstly methods to improve the haptic feedback performance of teleoperation are developed Secondly methods to stabilize adaptive shared control systems while still ensuring high teleoperation performance are proposed The methods are validated on multiple robotic systems and they were applied in several projects both in space and terrestrial domains With the aforementioned contributions this monograph provides an overarching framework to improve synergy between humans and robots The flexibility of the framework allows integration of existent teleoperation and shared control approaches which further promotes synergy within the robotics community

**Towards Affordance-Based Robot Control** Erich Rome, Joachim Hertzberg, Georg Dorffner, 2008-02-11 Today's mobile robot perception is insufficient for acting goal directedly in unconstrained dynamic everyday environments like a home a factory or a city Subject to restrictions in bandwidth computer power and computation time a robot has to react to a wealth of dynamically changing stimuli in such environments requiring rapid selective attention to decisive action relevant information of high current utility Robust and general engineering methods for effectively and efficiently coupling perception action and reasoning are unavailable Interesting performance if any is currently only achieved by sophisticated robot programming exploiting domain features and specialties which leaves ordinary users no chance of changing how the robot acts The purpose of this volume outcome of a GI Dagstuhl Seminar held in Dagstuhl Castle in June 2006 is to give a first overview on the concept of affordances for the design and implementation of autonomous mobile robots acting goal directedly in a dynamic environment The aim is to develop affordance based control as a method for robotics The potential of this new methodology will be shown by going beyond navigation like tasks towards goal directed autonomous manipulation in the project demonstrators

*A Hybrid Deliberative Layer for Robotic Agents* Ronny Hartanto, 2011-07-18 The Hybrid Deliberative Layer HDL solves the problem that an intelligent agent faces in dealing with a large amount of information which may or may not be useful in generating a plan to achieve a goal The information that an agent may need is acquired and stored in the DL model Thus the HDL is used as the main knowledge base system for the agent In this work a novel approach which amalgamates Description Logic DL reasoning with Hierarchical Task Network HTN planning is introduced An analysis of the performance of the approach has been conducted and the results show that this approach yields significantly smaller planning problem descriptions than those generated by current representations in HTN planning

**Autonomous Robots** Farbod Fahimi, 2008-10-25 It is at least two decades since the conventional robotic

manipulators have become a common manufacturing tool for different industries from automotive to pharmaceutical. The proven benefits of utilizing robotic manipulators for manufacturing in different industries motivated scientists and researchers to try to extend the applications of robots to many other areas by inventing several new types of robots other than conventional manipulators. The new types of robots can be categorized in two groups: redundant and hyper redundant manipulators and mobile ground marine and aerial robots. These groups of robots, known as advanced robots, have more freedom for their mobility which allows them to do tasks that the conventional manipulators cannot do. Engineers have taken advantage of the extra mobility of the advanced robots to make them work in constrained environments ranging from limited joint motions for redundant or hyper redundant manipulators to obstacles in the way of mobile ground marine and aerial robots. Since these constraints usually depend on the work environment, they are variable. Engineers have had to invent methods to allow the robots to deal with a variety of constraints automatically. A robot that is equipped with those methods is called an Autonomous Robot. Autonomous Robots Kinematics Path Planning and Control covers the kinematics and dynamic modeling analysis of Autonomous Robots as well as the methods suitable for their control. The text is suitable for mechanical and electrical engineers who want to familiarize themselves with methods of modeling analysis control that have been proven efficient through research.

*Control Problems in Robotics and Automation* Bruno Siciliano, Kimon P. Valavanis, 1998-01-20

Focusing on the important control problems in state of the art robotics and automation, this volume features invited papers from a workshop held at CDC San Diego, California. As well as looking at current problems, it aims to identify and discuss challenging issues that are yet to be solved but which will be vital to future research directions. The many topics covered include automatic control, distributed multi agent control, multirobots, dexterous hands, flexible manipulators, walking robots, free floating systems, nonholonomic robots, sensor fusion, fuzzy control, virtual reality, visual servoing and task synchronization. *Control Problems in Robotics and Automation* will be of interest to all researchers, scientists and graduate students who wish to broaden their knowledge in robotics and automation and prepare themselves to address and resolve the control problems that will be faced in this field as we enter the twenty first century.

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