PROGRAMME DE LA JOURNÉE DES JEUNES CHERCHEURS ET JEUNES CHERCHEUSES EN ROBOTIQUE

7 Novembre 2022

Campus Pierre et Marie Curie - Paris

9:00 - 9:15	Mot de bienvenue
9:15 - 9:30	Bio-inspired Robotic Finger with Adaptive Frictional Properties - Thomas Daunizeau, *INSTITUT DES SYSTÈMES INTELLIGENTS ET DE ROBOTIQUE*
9:30 - 9:45	Servo Electro-Hydraulic Actuator for Robotics Assistive Devices - Ghiath ABDULMALEK, *IBISC*
9:45 - 10:00	Allo-centric Occupancy Grid Prediction for Urban Traffic Scene Using Video Prediction Networks - Rabbia ASGHAR, *INRIA - EQUIPE CHROMA*
10:00 - 10:15	Automatic Verbal Depiction of a Brick Assembly for a Robot Instructing Humans - Rami Younes, *GRENOBLE IMAGES PAROLE SIGNAL AUTOMATIQUE, LABORATOIRE D'INFORMATIQUE DE GRENOBLE*
10:15 - 10:30	Path planning for 3-D in-hand dexterous micro-manipulation in presence of adhesion forces - Ivan TCHOUATAT KEPSEU, *FEMTO-ST, UNIVERSITÉ BOURGOGNE FRANCHE-COMTÉ*
10:30 - 11:00	Pause café
11:00 - 11:15	Towards Autonomous Robotic Behavior to Accommodate Human Variability - Belal HMEDAN, *LABORATOIRE D'INFORMATIQUE DE GRENOBLE - LIGLAB*
11:15 - 11:30	A quality-diversity approach to study the impact of human morphology in physics-based virtual workstations - Jacques Zhong, *LABORATOIRE DE SIMULATION INTERACTIVE (LSI), LABORATOIRE LORRAIN DE RECHERCHE EN INFORMATIQUE ET SES APPLICATIONS*
11:30 - 11:45	Autonomous tracking of a dynamic target by onboard acoustic imagery using an aerial drone: application on the detection of hornet nests - Badillo Leonardo
11:45 - 12:00	Attention management: Evaluating robot's gaze and/or head direction in a multi-party interaction. - Léa Haefflinger, *ATOS, GIPSA - COGNITIVE ROBOTICS, INTERACTIVE SYSTEMS, & SPEECH PROCESSING*
12:00 - 12:15	Gathering spatially and temporally spreading data with aerial robots - Hai-Nguyen Nguyen, *LAAS*
12:15 - 13:45	Pause déjeuner et Session Poster
13:45 - 14:00	AI-accelerated genetic algorithm with Bezier curve-based genotype for soft robot design - Loïc Mosser, *LABORATOIRE DES SCIENCES DE LÍNGÉNIEUR, DE LÍNFORMATIQUE ET DE LÍMAGERIE*
14:00 - 14:15	Localisation collaborative décentralisée avec mise à jour de carte utilisant le filtre de Schmidt-Kalman - Maxime Escourrou, *HEURISTIQUE ET DIAGNOSTIC DES SYSTÈMES COMPLEXES [COMPIÈGNE]*
14:15 - 14:30	Linear Model Predictive Control in SE(3) for online trajectory planning in dynamic workspaces - Nicolas Torres Alberto, *TEAM AUCTUS, STELLANTIS*
14:30 - 14:45	HATP/EHDA: A Robot Task Planner Anticipating and Eliciting Human Decisions and Actions - Anthony Favier, *LAAS-CNRS / ANITI*
14:45 - 15:45	Concours et Recherche Publique
15:45 - 16:15	Pause café
16:15 - 16:30	Matériaux souples et actifs pour la manipulation dextre robotisée - Manuela OTTI, *INSTITUT PASCAL*
16:30 - 16:45	Learning to Predict Action Feasibility for Task and Motion Planning in 3D Environments - Smail AIT BOUHSAIN , *LABORATOIRE D'ANALYSE ET D'ARCHITECTURE DES SYSTÈMES [TOULOUSE]*
16:45 - 17:00	Performance evaluation of an innovative suspension system for obstacle crossing - Denis N'CHOT, *INSTITUT PASCAL*
17:00 - 17:15	A Sensitivity-Aware Motion Planner (SAMP) to Generate Intrinsically-Robust Trajectories - Simon Wasiela, *LAAS-CNRS*
17:15 - 17:30	Quantifying the Human Motor Variability in a typical Industrial Task with a Collaborative Robot - Bousigues Raphaël
17:30 - 17:45	A 3D exoskeleton brace for treatment of scoliosis - Rahul RAY, *IUT DE BOURGES*
17:45 - 18:00	Discours de clôture

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