33rd Colloquium of Automation - AGENDA

Oct. 4 to Oct. 5, 2011 in Leer

1st Day

10:00     Arrival, preparation

10:50 - 11:00  Opening
Gräser, A., Michels, K. and Ristić-Durrant, D.

11:00 - 12:40  **Robot Vision / Computer Vision**
Grigorescu, S. M.  
*On Robust 3D Scene Perception and Camera Egomotion Estimation*

Natarajan, S. K.  
*Robust 3D Modelling of Real-World Objects*

Mata Alegre, V. and Hillers, B.  
*Statistical edge detector for metal surface localization during TIG welding*

Enjarini, B.  
*Planar Regions Segmentation and its Possible Applications in Service Robots*

12:40 – 13:10  Poster-Introduction (1 slide/poster)

13:10 – 14:30  Lunch

14:30 - 16:00  **Automation / Control / Product Design**
Weidemann, D. and Diekmann, R.  
*An Optimal Control Approach for Discrete Event Systems with Enforceable Events*

Leu, A.  
*Stereo Vision Based Collision Warning System for Automotive Applications*

Fotoohi, L.  
*On the Correctness and Simplification of Safety Specification in Service Robotics*

Hamadmad, R.  
*Personalized products in health care using generative manufacturing processes*

16:00 – 16:15  Coffee break

16:15 – 17:45  **Poster session**
Schüttler, J.  
*Ideas for a model-based leakage location system for district heating networks of old assembly*
Tetzel, T. and Hillers, B.
*A robust optical system for slag expulsion detection*

Heyer, S.
*Facial Expressions for Robot Control via Recognition of Changes*

Heyer, T.
*Return to Profession by means of Care-Providing Robot FRIEND*

Fragkopoulos, C.
*Designing Manipulative Skills for Library Scenarios*

Cocias, T. and Grigorescu, S. M.
*Object Surface Approximation using Generic Fitted Primitives*

Ristić-Durrant, D., Slavnić, S., Leu, A. and Gräser, A.
*CORBYS-Cognitive Control Framework for Robotic Systems*

Leu, A., Kuzmicheva, O., Ristić-Durrant, D. and Gräser, A.
*Reha@Home - Markerless vision system for gait rehabilitation at home*

Mota, A., Focke, S., Liu, X., Slavnić, S. and Leu, A.
*Design and development of CORBYS robot control architecture using open source-software platforms*

Ehlers, J.
*The influence of higher cognitive tasks on SSVEP activity*

Rünzi, S.
*Dynamic modelling of a gas turbine combined cycle power plant*

19:30 Buffet
2nd Day

07:30 - 09:00  Breakfast

09:00 - 10:15  Robotics

Heyer, T
*Intelligent context-aware Task-Planning using Object Anchoring*

Kampe, H.
*Programming by Demonstration for Scenarios in Service Robotics*

Wang, T.
*Grasp Planning for Rehabilitation Robot in Library Scenario*

10:15 – 10:30  Coffee break

10:30 - 12:10  BCI

Buchholz, S., Tamm, S., Heine, A. and Jacobs, A.
*The influence of head models on EEG source localization with beamformers*

Ren, Y. and Valbuena, D.
*Spatial Combination of EEG Signals for Robust SSVEP Detection*

Lüth, Thorsten
*SSVEP calibration using the BCI Wizard*

Malechka, T.
*sBCI – a hybrid brain-computer interface*

12:10 – 13:20  Lunch

13:30 - 13:50  Best Presentation, Best Poster, Closing Ceremony

14:00  Departure
Hints

- **Presentation**
  - Each presentation takes maximal 25 minutes
    (20 minutes presentation + 5 minutes discussion)

- **Poster**
  - The poster session is only on the first day. The poster must be placed there by each presenter on its own before the colloquium starts on Tuesday morning before the opening ceremonial.
  - In the poster introduction each presenter of a poster has to present the main issues in one slide in maximal 1 minutes. This slide must be sent till Monday, the 26th of September to colloquium@iat.uni-bremen.de.