Name: Informatik 6 - Lehrstuhl für Echtzeitsysteme und Robotik (Prof. Knoll)

Occurences:
• Hochschulbibliographie > 2017 > Fakultäten > Informatik
[1/106]: Brandenbourger, Benjamin and Vathoopan, Milan and Zoitl, Alois, Modeling and verifying behavioral constraints for automation systems, Industrial Informatics (INDIN), 2017 IEEE 15th International Conference on, 2017


[3/106]: Brandenbourger, Benjamin and Vathoopan, Milan and Zoitl, Alois, Generating metamodel-based descriptions of automation components in AutomationML, Industrial Technology (ICIT), 2017 IEEE International Conference on, 2017


[7/106]: Zied Tayeb, Emec Erçelik, Jörg Conradt, Decoding of motor imagery movements from EEG signals using SpiNNaker neuromorphic hardware, Neural Engineering (NER), 2017 8th International IEEE/EMBS Conference on, 2017

[8/106]: Wang, Xiebing; Cui, Mingyue; Huang, Kai; Knoll, Alois; Chen, Long, Improving the performance of ADAS application in heterogeneous context: A case of lane detection, 2017 IEEE 20th International Conference on Intelligent Transportation Systems (ITSC), IEEE, 2017


[10/106]: Gruber, Felix; Kim, Eric S.; Arcak, Murat, Sparsity-Aware Finite Abstraction, 2366-2371, IEEE 56th Annual Conference on Decision and Control (CDC), 2017


[12/106]: Nikhil Somani, Yaadhav Raaj, Suraj Nair, and Alois Knoll, Adapting the search subspace of a particle filter using geometric constraints, 2017


[18/106]: Jordan Ivanchev, Daniel Zehe, Suraj Nair, and Alois Knoll, Fast identification of critical roads by neural networks using system optimum assignment information, Intelligent Transportation Systems (ITSC), 2017

[19/106]: Morteza Hashemi Farzaneh, Stefan Kugele, and Alois Knoll, A graphical modeling tool supporting automated schedule synthesis for time-sensitive networking, 22nd IEEE International Conference on Emerging Technologies And Factory Automation (ETFA), 2017
[20/106]: Stefan Kugele, Vadim Cebotari, Mario Gleirscher, Morteza Hashemi Farzaneh, Christoph Segler, Sina Shafaei, Hans-Joerg Voegel, Fridolin Bauer, Alois Knoll, Diego Marmsoler, and Hans-Ulrich Michel, Research challenges for a future-proof e/e architecture - a project statement, 15. Workshop Automotive Software Engineering, 2017


[26/106]: Huang, Kai; Zhou, Mingchuan; Lajblich, Carolina; Lohmann, Chris P.; Knoll, Alois; Ling, Yehua; Lin, Haotian; Nasseri, M. Ali, A Flexible Head Fixation for Ophthalmic Microsurgery., 2017 Chinese Automation Congress (CAC), 2017

[27/106]: Ana Maria Radut, Sina Shafaei, A Regression-based Control Approach for Limited Slip Differential, 2017

[28/106]: Polikarpova, Nadia, Schneider, Steve, Formalising and monitoring traffic rules for autonomous vehicles in Isabelle/HOL, 2017


[31/106]: Yadong Xu, Wentong Cai, David Eckhoff, Suraj Nair, and Alois Knoll, A graph partitioning algorithm for parallel agent-based road traffic simulation, Annual ACM Conference on SIGSIM Principles of Advanced Discrete Simulation (SIGSIM-PADS '17), 2017


[33/106]: Alois Knoll, Florian Röhrbein, Alexander Kuhn, Mahmoud Akl, and Kenny Sharma, Neurorobotics, Informatik-Spektrum, 2017

[34/106]: Pereira, A.; Althoff, M., A cartesian-space method for calculating human reachable occupancy, Technische Universität München, 2017


[36/106]: Biao Hu, Kai Huang, Gang Chen, Long Cheng, Dongkun Han, and Alois Knoll, Schedulability analysis towards arbitrarily activated tasks in mixed-criticality systems, Circuits, Systems and Computers, 2017

[37/106]: Biao Hu, Kai Huang, Gang Chen, Long Cheng, and Alois Knoll, Online workload monitoring with the feedback of actual execution time for real-time systems, in Design, Automation and Test in Europe (DATE), 2017
[38/106]: David Eckhoff, Daniel Zehe, Jordan Ivanchev, and Alois Knoll, Smart City-to-Vehicle - Measuring, Prediction, Influencing, ATZelektronik worldwide, 2017


[40/106]: Kirill Dorofoev, Chih-Hong Cheng, Magno Guedes, Pedro Ferreira, Stefan Profanter, and Alois Zoitl, Device adapter concept towards enabling plug&produce production environments, Proceedings of the IEEE International Conference on Emerging Technologies And Factory Automation (ETFA), 2017

[41/106]: Gulati, Dhiraj; Zhang, Feihu; Clarke, Daniel; Knoll, Alois, Graph based cooperative localization using symmetric measurement equations and dedicated short range communication, 2017 IEEE International Conference on Multisensor Fusion and Integration for Intelligent Systems (MFI), 2017

[42/106]: Gulati, Dhiraj; Sharif, Uzair; Zhang, Feihu; Clarke, Daniel; Knoll, Alois, Data association - solution or avoidance: Evaluation of a filter based on RFS framework and factor graphs with SME, 2017 IEEE International Conference on Multisensor Fusion and Integration for Intelligent Systems (MFI), 2017


[44/106]: Gulati, Dhiraj; Zhang, Feihu; Malovetz, Daniel; Clarke, Daniel; Knoll, A., Robust cooperative localization in a dynamic environment using factor graphs and probability data association filter, 2017 20th International Conference on Information Fusion (Fusion), 2017

[45/106]: Gulati, Dhiraj; Zhang, Feihu; Malovetz, Daniel; Clarke, Daniel; Hinz, Gereon; Knoll, Alois, Graph based vehicle infrastructure cooperative localization, 2017 20th International Conference on Information Fusion (Fusion), 2017

[46/106]: Gulati, Dhiraj; Zhang, Feihu; Clarke, Daniel; Knoll, Alois, Graph-Based Cooperative Localization Using Symmetric Measurement Equations, Sensors, 2017, 17, 6


[49/106]: Zhou, Mingchuan; Huang, Kai; Eslami, Abouzar; Zapp, Daniel; Lin, Haotian; Maier, Mathias; Lohmann, Chris P.; Knoll, Alois; Nasseri, M. Ali, Beveled Needle Position and Pose Estimation based on Optical Coherence Tomography in Ophthalmic Microsurgery, 2017 IEEE International Conference on Robotics and Biomimetics, 2017

[50/106]: Zhou, Mingchuan; Roodaki, Hessam; Eslami, Abouzar; Chen, Guang; Huang, Kai; Maier, Mathias; Lohmann, Chris P.; Knoll, Alois; Nasseri, M. Ali, Needle Segmentation in Volumetric Optical Coherence Tomography Images for Ophthalmic Microsurgery, Applied Sciences, 2017

[51/106]: Lu, Jinzhu; Zhou, Mingchuan; Gao, Yingwang; Jiang, Huanyu, Using hyperspectral imaging to discriminate yellow leaf curl disease in tomato leaves, Precision Agriculture, 2017, 1–16

[52/106]: Xiao, Shanshan; Bing, Zhenshan; Huang, Kai; Huang, Yuhong, Snake-like Robot Climbs Inside Different Pipes, 2017 IEEE International Conference on Robotics and Biomimetics, 2017


[54/106]: Kraft, Martin; Rickert, Markus, How to Teach Your Robot in 5 Minutes: Applying UX Paradigms to Human-Robot-Interaction, Proceedings of the IEEE International Symposium on Robot and Human Interactive Communication (RO-MAN), 2017

[55/106]: Chen, Chao; Rickert, Markus; Knoll, Alois, Motion Planning under Perception and Control Uncertainties with Space Exploration Guided Heuristic Search, Proceedings of the IEEE Intelligent Vehicles Symposium (IV), 2017


[57/106]: Pfisterer, Jonas H. K.; Liang, Yunchang; Schneider, Oliver; Bandarenka, Aliaksandr S., Direct instrumental identification of catalytically active surface sites, Nature, 2017, 549, 7670, 74-77

[59/106]: Cheng, Long; Bing, Zhenshan; Knoll, Alois; Huang, Kai, Biologically Inspired Spiking Neural Network for Autonomous Locomotion Control of Snake-Like Robots, International Journal of Biosensors & Bioelectronics, 2017

[60/106]: Hinz, Gereon; Chen, Guang; Aafaque, Muhammad; Rohrbein, Florian; Conradt, Jorg; Bing, Zhenshan; Qu, Zhongnan; Stechel, Walter; Knoll, Alois, Online Multi-Object Tracking-by-Clustering for Intelligent Transportation System with Neuromorphic Vision Sensor, the 40th German Conference on Artificial Intelligence(KI 2017), 2017

[61/106]: Jiang, Zhuangyi; Bing, Zhenshan; Huang, Kai; Chen, Guang; Cheng, Long; Knoll, Alois, Event-based Target Tracking Control for a Snake Robot Using a Dynamic Vision Sensor, International Conference On Neural Information Processing (ICONIP), 2017


[63/106]: Chen, Guang; Bing, Zhenshan; Roehrbein, Florian; Conradt, Jorg; Huang, Kai; Cheng, Long; Jiang, Zhuangyi; Knoll, Alois, Toward Brain-inspired Learning with the Neuromorphic Snake-like Robot and the Neuorobotic Platform, IEEE Transactions on Cognitive and Developmental Systems, 2017, 1-1

[64/106]: Bing, Zhenshan; Cheng, Long; Knoll, Alois; Zhong, Anyang; Huang, Kai; Zhang, Feihu, Slope angle estimation based on multi-sensor fusion for a snake-like robot, 2017 20th International Conference on Information Fusion (Fusion), IEEE, 2017

[65/106]: Bing, Zhenshan; Cheng, Long; Huang, Kai; Zhou, Mingchuan; Knoll, Alois, CPG-based control of smooth transition for body shape and locomotion speed of a snake-like robot, 2017 IEEE International Conference on Robotics and Automation (ICRA), IEEE, 2017

[66/106]: Bing, Zhenshan; Cheng, Long; Chen, Guang; Röhrbein, Florian; Huang, Kai; Knoll, Alois, Towards autonomous locomotion: CPG-based control of smooth 3D slithering gait transition of a snake-like robot, Bioinspiration & Biomimetics, 2017, 12, 3, 035001

[67/106]: Ames, Aaron D.; Tabuada, Paulo; Jones, Austin; Ma, Wen-Loong; Rungger, Matthias; Schürmann, Bastian; Kolathaya, Shishir; Grizzle, Jessy W., First steps toward formal controller synthesis for bipedal robots with experimental implementation, Nonlinear Analysis: Hybrid Systems, 2017, 25, 155 - 173


[69/106]: Hisch, F.; Giusti, A.; Althoff, M., Robust Control of Continuum Robots using Interval Arithmetic, Proc. of the 20th World Congress of the International Federation of Automatic Control, accepted, 2017


[71/106]: Schürmann, Bastian; Althoff, Matthias, Guaranteeing Constraints of Disturbed Nonlinear Systems Using Set-Based Optimal Control in Generator Space, Proc. of the 20th World Congress of the International Federation of Automatic Control, 2017

[72/106]: Schürmann, Bastian; Althoff, Matthias, Convex Interpolation Control with Formal Guarantees for Disturbed and Constrained Nonlinear Systems, Proc. of Hybrid Systems: Computation and Control, Best Repeatability Award and Finalist for Best Student Paper Award, 2017

[73/106]: Schürmann, Bastian; Heß, Daniel; Eilbrecht, Jan; Stursberg, Olaf; Köster, Frank; Althoff, Matthias, Ensuring Driveability of Planned Motions Using Formal Methods, Proc. of the 20th IEEE International Conference on Intelligent Transportation Systems, 2017

[74/106]: Schürmann, Bastian; Althoff, Matthias, Optimal Control of Sets of Solutions to Formally Guarantee Constraints of Disturbed Linear Systems, Proc. of the American Control Conference, 2017

[75/106]: Rizaldi, Albert; Keinholz, Jonas; Huber, Monika; Feldle, Jochen; Immner, Fabian; Althoff, Matthias; Hilgendorf, Eric; Nipkow, Tobias, Formalising and Monitoring Traffic Rules for Autonomous Vehicles Involving Multiple Lanes in {Isabelle/HOL}, Proc. of the 13th International Conference on integrated Formal Methods, accepted, 2017
[76/106]: Pereira, Aaron; Althoff, Matthias, Online Formal Verification of Robot Trajectories for Guaranteed Safety of Humans, ICRA-PlanRob-2017, 2017


[78/106]: Pek, C.; Zahn, P.; Althoff, M., Verifying the Safety of Lane Change Maneuvers of Self-driving Vehicles Based on Formalized Traffic Rules, Proc. of the IEEE Intelligent Vehicles Symposium, 2017


[86/106]: Kopetzki, Anna-Kathrin; Schürmann, Bastian; Althoff, Matthias, Efficient Methods for Order Reduction of Zonotopes, Proc. of the 56th IEEE Conference on Decision and Control, 2017


[88/106]: Giusti, A.; Malzahn, J.; Tsagarakis, N. ~G.; Althoff, M., Combined Inverse-Dynamics/Passivity-Based Control for Robots with Elastic Joints, Proc. of the IEEE International Conference on Robotics and Automation, 2017


[90/106]: El-Guindy, Ahmed; Schaab, Konstantin; Schürmann, Bastian; Han, Dongkun; Stursberg, Olaf; Althoff, Matthias, Formal LPV Control for Transient Stability of Power Systems, Proc. of the IEEE PES General Meeting, 2017


[94/106]: Calzolari, Davide; Schürmann, Bastian; Althoff, Matthias, Comparison of Trajectory Tracking Controllers for Autonomous Vehicles, Proc. of the 20th IEEE International Conference on Intelligent Transportation Systems, 2017

[95/106]: Beckert, D.; Pereira, A.; Althoff, M., Online Verification of Multiple Safety Criteria for a Robot Trajectory, Proc. of the 56th IEEE Conference on Decision and Control, 2017


[98/106]: Söntges, S.; Althoff, M., Computing Possible Driving Corridors for Automated Vehicles, Proc. of the IEEE Intelligent Vehicles Symposium, 2017

[99/106]: Althoff, Matthias; Koschi, Markus; Manzinger, Stefanie, CommonRoad: Composable benchmarks for motion planning on roads, Proc. of the IEEE Intelligent Vehicles Symposium, 2017

[100/106]: Koschi, Markus; Althoff, Matthias, SPOT: A tool for set-based prediction of traffic participants, Proc. of the IEEE Intelligent Vehicles Symposium, 2017


[103/106]: Chen, Guang, Efficient 3D Human Motion Perception System with Un-supervision, Randomization and Discrimination, 2017, Dissertation, 133 Seiten

