



Workshop Projet ROSACE

(Robots et Systèmes Auto-adaptatifs Communicants Embarqués)

February 12, 2010

Auditoium - IRIT

9h00 Welcome

9h15 *ROSACE: a short presentaion of the project* (Rachid Alami)

9h30 *General Information Quality-Based Approach for Satisfying Sensor Constraints in Tightly-Coupled Multi-Robot Task* (Lynn Parker, University of Tennessee)

10h15 Coffee Break

10h35 *Control architectures and paradigms for multi-robot cooperation* (Félix Ingrand)

Hierarchical task allocation with time and communication constraints (Simon Lacroix)

11h10 *Cooperative multi-agent systems* (Pierre Glize)

11h 45 *ORS: the OpenRobots Simulator* (Gilberto Escheveria)

12h20 Lunch

13h45 *Automatic Generation of Control and Diagnostics Code for Distributed Embedded Systems* (Gregory Provan, University College Cork)

14h30 *Embedded systems issues and assessability* (Christel Seguin)

UAV testability (Christel Seguin)

15h05 *Distributed robotic functions* (Michel Devy)

Active Detection and Tracking by a UAV (Yoko Watanabe)

15h40 Coffee break

16h00 *Adaptability management for autonomous mobile group communication* (Khalil Drira)

16h35 Round table (coordinated by Marie-Pierre Gleizes and Patrick Fabiani)

17h30 End