

Workshop on Robust Optimization-Based Control and Planning for Legged Robots, ICRA 2016

08:00 - 08:15	Introduction	
08:15 - 08:45	Andrea Del Prete	Robustness to Joint-Torque Tracking Errors in Task-Space Inverse Dynamics
08:45 - 09:15	Boris Houska	Nonlinear and robust MPC with applications in robotics
09:15 - 09:45	Melanie Zeilinger	Robust Model Predictive Control - Performance and Constraint Satisfaction under Uncertainties
09:45 - 10:15	Francesco Nori	Robust whole-body dynamics estimation
10:15 - 11:00	Coffee break	
11:00 - 11:30	Richard Oberdieck	Robust Multi-Parametric Model-based Optimization & Control
11:30 - 12:00	Ludovic Righetti	Improving legged robots performance through the control of contact interactions and sensor-fusion
12:00 - 12:45	Round table 1	
12:45 - 13:45	Lunch break	
13:45 - 14:15	Emo Todorov	Full-Body Dynamic Motion Planning that Transfers to Physical Humanoids
14:15 - 14:45	Salman Faraji	3LP walking model: a Fresh Breath for optimizations
14:45 - 15:15	Kris Hauser	Iterative trajectory optimization with learned contact friction
15:15 - 15:45	Coffee break	
15:45 - 16:15	Didier Henrion	The Lasserre hierarchy in robotics
16:15 - 16:45	Michael Posa	Stability analysis and control design with impacts and friction
16:45 - 17:15	Amir Ali Ahmadi	DSOS and SDSOS optimization: more tractable alternatives to SOS optimization
17:15 - 18:00	Round table 2	