

Monday, April 7, 2008

8.00-24.00 *Arrival and accommodation of participants*

Tuesday, April 8, 2008

8.00-10.00 *Registration of participants*
Entry of the Conference Hall (2nd floor)

10.00-11.30 **Plenary Session**
Conference Hall (2nd floor)

11.30-12.00 *Coffee-break*

12.00-13.30 *Plenary Session (continuation)*

13.30-14.30

Lunch

Dining Room (1st floor)

14.30-16.00	Section 1 Theory, calculation, and design Conference Hall	Section 2 Robotic systems and their application Room 208	Section 3 Control systems Room 401	Section 4 Information aspects and sensors Room 209	Section 5 Components of robotic systems Room 325	ISTC Special Session <i>Minor Conference</i> <i>Hall (room 301)</i>
16.00-16.30	Coffee-break					
16.30-18.00	Section 1 (continuation)	Section 2 (continuation)	Section 3 (continuation)	Section 4 (continuation)	Section 5 (continuation)	ISTC Special Session (continuation)

Wednesday, April 9, 2008

10.00-11.30	Section 1 Theory, calculation, and design Conference Hall (2 nd floor)	Section 2 Robotic systems and their application Room 208	Section 3 Control systems Room 401	Section 4 Information aspects and sensors Room 209	Section 5 Components of robotic systems Room 325	ISTC Special Session Minor Conference Hall (room 301)
11.30-12.00	Coffee-break					
12.00-13.30	Section 1 (continuation)	Section 2 (continuation)	Section 3 (continuation)	Section 4 (continuation)	Section 5 (continuation)	
12.00-13.30	<i>Visit to demo zone and test bed RTC</i>					
13.30-14.30	Lunch <i>Dining Room(1st floor)</i>					
14.30-16.00	Closing Session Conference Hall					
16.00-16.30	Coffee-break					
16.30-17.30	Closing Session (continuation) Conference Hall					

Tuesday, April 8

- 10.00-10.30** **Conference opening** *Conference Hall*
Lopota V.A., Director and Chief Designer of CRDI RT, President and Chief Designer of Russian Space Corporation “Energia” after Korolev S.
- Welcoming speeches to Conference participants**
Tereshchenko G.F., Vice-chairman of the Presidium of Russian Academy of Sciences St-Petersburg Scientific Center
Dikiy V.A., Chief of the Robotics Department of EMERCOM of Russia
Kuchinsky E.V., Major-General of Russian Ministry of Defense
Burkhard Endrullat, General Project Manager International Science and Technology Center (ISTC)
Kalyaev I.A., Corresponding Member of Scientific Center of Russian Academy of Sciences
Arseniev D.G., First Pro-rector of St-Petersburg State Polytechnical University
Suvorinov A.V., Head of Department of Federal Agency of Science and Innovations
Victorov A.V., Chairman of St-Petersburg Government Science and High Education Committee
- 10.30-13.30** **Plenary Session** *Conference Hall*
The Chairman – professor Yurevich E.I.
The secretary – Korsakov A.M.
- 10.30-11.30** **40 Years Anniversary of CRDI RTC**
Yurevich E.I., professor, CR&DI RTC, Saint-Petersburg
- Modern State and Development Prospects of Domestic Space Robotics**
Minakov E.P., Lopota V.A., Yurevich E.I., CR&DI RTC, Saint-Petersburg
- New Developments of Scientific-and-Educational Center of Robotics of the MSTU n.a. N. E. Bauman**
Maksimov A.A., Yuschenko A.S., Kalinichenko S.V., Zenkevich S.L., Mikhailov B.B., MSTU n.a. N. Bauman, Moscow
- 11.30-12.00** *Coffee-break*

12.00-13.30 Energy Foraging of Robot Swarm and Symbiotic Robot Organism

Kernbach S., Levi P., Kernbach O., University of Stuttgart, Germany

Wall climbing Robots for extreme environments

Gradetsky V.G., IPMech RAS, Moscow

Problems of Experimental Robot-Automobile Creation

Makarov I.M., MIREA (TU), Moscow

Ignatjev M.B., Makin P.I., Uljanov B.G., Saint-Petersburg State University of Aerospace Instrumentation, Saint-Petersburg

Tuesday, April 8

14.30-18.00

Wednesday, April 9

10.00-13.30

Section 1: Theory, Calculation and Design

Conference Hall

The head – professor Shirjaev V.I., professor Smolnikov B.A.

The secretary – Korsakov A.M.

1.1. Adaptive behavior networks for robot control

Stankevich L. A., SPII RAS, Saint-Petersburg

1.2. Dynamics of Search-and-Rescue Underwater Vehicle and Its Systems in Various Operation Modes

Trunov A.N., Petr Mogila National Humanitarian University, Nikolaev, Ukraine

1.3. Ensuring Mobile Robots Autonomy

Ermolov I.L., Moscow State University of Technology «STANKIN», Moscow

1.4. Research of mobile minirobot dynamics during the getting over obstacles

Shinov S.N., MSTU n.a. N. Bauman, Moscow

1.5. Reconfigurable Systems Based on Mechatronic Modules for Monitoring, Rescue, and Technological Operations in Extreme Conditions

Burdakov S.F., Kirichenko V.V., Timofeev A.N., Kotova E.L., Kapustin V.A., CR&DI RTC, Saint-Petersburg

1.6. System Design of Intelligent Systems of Logical-Dynamical Class

Timchenko A.A., Podgornij N.V., Melkin V.P., Cherkasy State Technological University, Ukraine

1.7. Design of Built-in Electromechanical Executive Robotic Devices

Gollandzev U.A., Lola S.A., SPbSPU, Saint-Petersburg

1.8. Research of profile practicability of walking machine «Vosminog»

Frolova N.E., Pokrovskij D.N., Volgograd State Technical University, Volgograd

1.9. Mechanism for Bionic Robot-Lizard

Kanishchev V.I., Vologdina Ja. S., Sostovskij E.M., SMTU, Saint-Petersburg

1.10. Methods and algorithms of collective control of robots at their group application

Kapustyan S.G., SRI MCS TSFU, Taganrog

1.11. On friction of sliding, rotation and rolling

Karapetyan A.V., MSU by M. Lomonosov, Moscow

1.12. Dynamics of three-wheels mobile platform

Salmina M.A., Karapetyan A.V., MSU by M. Lomonosov, Moscow

1.13. Logical probabilistic simulation of the complicated robotic systems

Gorodetsky A.E., Tarasova I.L., IPME RAS, Saint-Petersburg

1.14. Simulation of the Dynamics of Robots

Pavlov B.I., Mechanical Engineering Research Institute n. a. A.A. Blagonravov, RAS, Moscow

1.15. Simulation Of Mobile Robot Moving Along Arbitrary Oriented Planes

Malyhin A.U., MSTU N.A. N. Bauman, Moscow

1.16. The Means Of The Retention Of The Wall Climbing Robots On Surfaces

Varfolomeev D.S., Korotkov A.L., CR&DI RTC, Saint-Petersburg

1.17. On the application of the redundend coordinats method for the mechatronic systems modeling

Krasinsky A.Ja., Kayumova D.R., Khalikov A.A., MSU, Moscow

1.18. Mixed simulation of DC motor using MATLAB environment

Goncharenko K.V., Poleschuk A.V., MSTU n.a. N. Bauman, Moscow

1.19. Modeling of a dynamic variation working zones of a link of mechanisms of parallel

Egorov I.N., Vladimir State University (VSU), Vladimir

Kadhim Houssain (The republic of Iraq), Vladimir State University (VSU), Vladimir

Tuesday, April 8

14.30-18.00

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Section 2. Robotic Systems and Their Application

Room 208

The head – professor Korolev V.A., professor Potapov A.M.

The secretary – Popov A.V.

2.1. Robotized Automatic Device for Ecological State Monitoring of Water Areas of Harbors and Ports

Zhukov Y.I., Skvortsov D.A., SMTU, Saint-Petersburg

2.2. Hull Identification System for Marine Autonomus Robotics (HISMAR)

Balashov M.V., MOSCOW STATE UNIVERSITY OF TECHNOLOGY «STANKIN»,

Moscow

2.3. Fault-Tolerant Architecture of Autonomous Unmanned Underwater Vehicles

Inzartsev A.V., Lvov O.Y., Institute of Marine Technologies problems– Far Eastern Department of RAS, Vladivostok

2.4. Robots for Underground Construction

Glebov N.A., Markijanov A.A., Uzhno-Rossiysky State Technical University (Novochoerkassk polytechnic University), Novochoerkassk

2.5. Mobile Complex for Conditions Monitoring Based on Small-Sized Aeronautic Vehicles of Balloon Type

Bulaev O.A., Kondratyev A.S., Minakov E.P., CR&DI RTC, Saint-Petersburg

2.6. Development of Complexes for Observation, Detection, and Identification Based on Small-Sized Robotized Air Vehicles

Gryaznov N.A., Kirichenko V.V., Sokolov E.I., Fedorov A.F., CR&DI RTC, Saint-Petersburg

2.7. The Microsystem Avionics of Smallsize Pilotless Aircraft

Raspopov V.Y., Yovkach S.E., Alaluev R.V., Tula State University, Tula

2.8. Problem of Decreasing of Near-Earth Space Environment Pollution Level and Robotic Aspects of Its Solution

Bulaev O.A., Kondratyev A.S., Minakov E.P., CR&DI RTC, Saint-Petersburg

2.9. On the problems of extreme robotics in processing industry

Scherbina B.V., Moscow State University of Applied Biotechnology, Moscow

2.10. Autonomous Mobile Robot

Roshchupkin S.A., Vorotnikov S.A., MSTU n.a. N. Bauman, Moscow

2.11. Mobile Robotic Complexes of Light and Superlight Classes for Special Purposes

Zelentsov V.V., Medvetsky S.V., Kosmachev P.V., Kudryashov V.B., Kovalenko V.A., MSTU n.a. N. Bauman, Moscow

2.12. Emergent multi connected FMS and its influence on transition of economy in the homogeneous industry

Darovskih V.D., Kyrgyz State Technical University n.a. I. Razzakov, Kyrgyzstan

2.13. Russian Project of Android Robots and Problems of Extreme Robotics

Permyakov A.F., Magazov S.S., Android Robotics Close Corp., Moscow

2.14. Development of Embedded Control Systems for Artificial Pulmonary Ventilation Equipment

Vasiliev A.E., SPbSPU, Saint-Petersburg

Sazonov I.A., «Krasnogvardeets» Public Corp., Saint-Petersburg

2.15. Prospects of Perfusion Mechatronic Systems Application in Medicine of Critical States

Kirichenko V.V., Kondratyev A.S., Pryadko A.I., Senchik K.Y., Modyagin A.I., CR&DI RTC, Saint-Petersburg

2.16. Algorithms of Biotechnical Control of Robots for Restorative Medicine

Arhipov M.V., Moscow state industrial university, Moscow

2.17. Algorithms of Position-and-Force Robot Control for Restorative Medicine

Zhuravlev V.V., Golovin V.F., Moscow state industrial university, Moscow

2.18. Adaptive control of pulse sequence in artificial circulation system

Mitrenin V.B., CR&DI RTC, Saint-Petersburg

Polyansky A.V., Cherepovets State University, Cherepovets

2.19. Medical systems: quality and safety in robotic surgery

Trunov A.N., Volkova S.O., Petr Mogila National Humanitarian University, Nikolaev, Ukraine

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Section 3. Control Systems

Room 401

The head - corresponding member of RAS Kalyaev I.A., professor Burdakov S.F.

The secretary – Modyagin A.N.

3.1. On Dynamic Objects Control Tasks under Information Deficiency

Shiryayev V.I., South Ural State University, Chelyabinsk

3.2. Robot – manipulator trajectory planning with dynamic error correction based on feed - forward neural networks

Glazkov V.P., Egorov I.V., Pchelintseva S.V., Saratov State Technical University, Saratov

3.3. Intelligent control of the robotic systems based on visual tracking system and fuzzy logic

Baranov D.N., Poduraev Y.V., Moscow State University of Technology «STANKIN», Moscow

3.4. Neuro-Fuzzy Control of Three-Mass Electromechanical Object with Bi-Resonant Elastic Deformations

Putov V.V., St-Petersburg State Electrical University, Saint-Petersburg

Zung Ch.A., Fjong V.K. (The Republic of Vietnam), St-Petersburg State Electrical University, Saint-Petersburg

3.5. Predictive Model Based Neural Network Control System of Mechatronic Ultrasonic Motor Unit

Lebedev A.Y., MSTU n.a. N. Bauman, Moscow

3.6. Control system of dynamic object using information from computer video system

Krasnikov S.V., MSTU n.a. N. Bauman, Moscow

3.7. Realization of Sinergetic Control Principles on Executive Level of Mobile Mechatronic Systems

Kleban V.O., Shalyto A.A., The State University of Information Technologies, Mechanics and Optics, Saint-Petersburg

3.8. Realization of Sinergetic Control Principles on Executive Level of Mobile Mechatronic Systems

Vasiliev A.E., Kriushov A.V., Shilov M.M., SPbSPU, Saint-Petersburg

3.9. Parameter control system of gait of the walking machine with cycle propellers

Briskin E.S., Sharonov N.G., Volgograd State Technical University, Volgograd

3.10. Control of movement and dynamics of wheel modules of mobile robot for Gas pipelines system

Kadhim Dergaam A. (The republic of Iraq), Vladimir State University (VSU), Vladimir

3.11. The Synthesis Of Locomotion Modes Of The Snakelike Robot On A Base Running Waves Composition

Ivanov A.A., Demidov D.A., Shmakov O.A., CR&DI RTC, Saint-Petersburg

3.12. Distribution Laws of Telecontrolled Underwater Robot in Near-Field Region of Observation Object

Kanishchev V.I., Petrov V.G., SMTU, Saint-Petersburg

3.13. Space Manipulator Path Planning for Earth Remote Sensing Camera Aiming with Simultaneous Spacecraft Attitude Stabilization

Leskov A.G., Karandaev A.A., MSTU n.a. N. Bauman, Moscow

3.14. Position-and-Force Control System for Space Manipulators

Popov A.V., CR&DI RTC, Saint-Petersburg

3.15. Position-force positional control and attitude of a gantry hexapod with PID-regulator at the executive level

Egorov I.N., Vladimir State University (VSU), Vladimir

Kadhim Houssain (The republic of Iraq), Vladimir State University (VSU), Vladimir

3.16. Method of Semi-Automatic Positioning Control of Manipulator with Assistance of Movable TV-Camera

Filaretov V.F., Katsurin A.A., IACP FEB RAS, Vladivostok

3.17. Manual control of two-arm manipulation robot by disconnecting handles

Kuptsov E.A., MSTU n.a. N. Bauman, Moscow

3.18. Speech control of mobile robot

Zhonin A.A., MSTU n.a. N. Bauman, Moscow

3.19. Application of the collective control method for rise of fault tolerance onboard is information-controlling systems of robotized vehicles

Kapustyan S.G., SRI MCS TSFU, Taganrog

3.20. Concept of Intelligent Mobile Robot Control Software

Kirsanov K.B., Levinsky B.M., Pryanichnikov V.E., Andreev V.P., “Sensorika” laboratory, M.V.Keldysh IAM RAS, Russian State Humanitarian University, Moscow

3.21. Driver and client-server software for RTOS QNX

Goncharenko K.V., Kurenev P.N., MSTU n.a. N. Bauman, Moscow

3.22. New Technology Application in Radio Communication Technique To Solve Problem of Remote Robot Control Under Extreme Conditions

Korsharovsky S.I., MIREA (TU), Moscow

3.23. Algorithm and components of board computer system for control of track telecamera of underwater robots

Kondratenko Y.P., Petr Mogila National Humanitarian University, Ukraine

Kondratenko V.Y., Kiev Scientific Institute n.a. Shevchenko, Kiev, Ukraine

Al-Suod Mahmoud Mohammad Salem, Romanov D.A., Scientific and Educational Complex n.a. Makarov, Kiev, Ukraine

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Section 4. Information Aspects and Sensors

Room 209

The head – professor Erosh I.L., professor Yuschenko A.S.

The secretary – Shumilov V.M.

4.1. Evolution and Prospects of Information-and-Control Systems Development in Robotics and Mechatronics

Timofeev A.V., SPII RAS, Saint-Petersburg

4.2. The multifunctional application of 3D models in the autonomous mobile robot dataware

Sukhoruchkina O.N., National Academy of Sciences of Ukraine Ministry of Education of Ukraine

4.3. Methodology of creation departmental digital telecommunication network

Odnoromanenko S.G., Cherkasy State Technological University, Ukraine

4.4. Problems of TVS Development for Extreme Robotic Systems

Bunyakov V.A., Yurevich E.I., CR&DI RTC, Saint-Petersburg

4.5. Method of multiple frames supersolution for guard television systems

Feofanov K.V., SPbSPU, Saint-Petersburg

4.6. Blind signal extraction method for system of diode parameters measurement

Kartamyshev A.V., SPbSPU, Saint-Petersburg

4.7. Identification motion noise parameters Algorithm for technological objects using computer vision system

Matloob Muhanad (The Republic of Iraq), Vladimir State University (VSU), Vladimir

4.8. About arrangement of radio beacons in system of near navigation of robots for maintenance of characteristics of accuracy

Shiryaev V.I., Elsakov S.M., Uzhno-Ural State University, Chelyabinsk

4.9. Computer video system for calculating of the motion path of mobile robot and for work space monitoring

Gurov A.B., Mikhajlov B.B., MSTU n.a. N. Bauman, Moscow

4.10. Portable chromatograph analyzer of the gas composition as the sensor

system for extreme robotics application

Zakharov S.A., Kirichenko V.V., Nerovnya L.K., Senchik K.Y., CR&DI RTC, Saint-Petersburg

4.11. Mobile robot sensor fusion

Zenkevich S.L., Minin A.A., MSTU n.a. N. Bauman, Moscow

4.12. Performance Control of Robotic Systems Under Extreme Conditions

Korshakovskiy S.I., Krasnenkov M.A., MIREA (TU), Moscow

4.13. Automatized Services and Mobile Robots

Kleban V.O., Shalyto A.A., The State University of Information Technologies, Mechanics and Optics, Saint-Petersburg

4.14. The Visualizer of the Work Operations of Manipulation Robots CAD Prototypes

Ivanov A.A., Grigorenko E.V., CR&DI RTC, Saint-Petersburg

4.15. Algorithm for a problem of getting information about forbidden configurations of a manipulator when it hits a cylinder, located on a horizontal surface

Ryabov O.N., Siberian Federal University, Krasnoyarsk

4.16. Multiprocessor Computing Structures with Dynamically Reconfigurable Architecture Based on FPGA

Kalyaev I.A., Levin I.I., SRI MCS TSFU, Taganrog

4.17. Methodology of Automated Synthesis of Built-in Inspection Tools of Digital Systems Based on Specification

Rupanov V.Y., Filippov A.S., SPbSPU, Saint-Petersburg

Tuesday, April 8

14.30-18.00

Wednesday, April 9

10.00-13.30

Section 5. Components of Robotic Systems Room 325

The head – professor Poduraev Y.V., professor Ivanov A.A.

The secretary – Babina I.I.

5.1. Mechatronic executive systems of direct act on the basis of linear synchronous motors of cylindrical and flat configuration

Mironov S.M., Goncharov A.S., Limited Liability company “Research and Development Institute – Scientific Center “Alfa”, Voronezh

5.2. Electropneumatic positional drives on the basis of predictive models for problems of a robotics

Ilyhin Y.V., Arfikuan S.A., Moscow State University Of Technology «STANKIN», Moscow

5.3. Development of Electropneumatic Servo Drives for Transport Robots Based on Mechatronic Components

Kharchenko A.N., Moscow State University Of Technology «STANKIN», Moscow

5.4. Microsystems bimorph actuator for space microrobust device

Korpuhin A.S., Zhukov A.A., Grinkin E.A., Federal State Unitary Enterprise “Russian Institute of Space Device Engineering”, Moscow

5.5. The self-organization optimal regulator for servo-motor control

Djachenko A.A., SRI MCS TSFU, Taganrog

5.6. Minimization of capacity of drive engine of cycle mechanisms of walking

Briskin E.S., Kalinin Ja.V., Volgograd State Technical University (Volg STU), Volgograd

5.7. To calculation of EFFICIENCY of wave robots of systems

Strekalov S.D., Limited Liability company “Center of Innovations – All-Russian Agricultural Academy”, Volgograd

5.8. Micromechanical Sensors and Modules for Extreme Robotics. New Developments and Applications

Gryazin D.G., Nesenyuk L.P., CR&DI “Electropribor”, Saint-Petersburg

5.9. Non-Traditional Executive Devices Based on Halbach Magnetic System

Vorobjov D.A., SPbSPU, Saint-Petersburg

5.10. Study of Sensitized Piezoelectric Gripper

Krushinsky I.A., Smirnov A.B., Ulanov V.N., SPbSPU, Saint-Petersburg

5.11. Mathematical Model of the Test Bench Designed for Frequency Characteristics Estimation of Micromechanical Gyros

Evseev V.O., CR&DI “Electropribor”, Saint-Petersburg

5.12. Investigation of Influence of Technological Spread of Micromechanical Gyroscope Parameters on Device Characteristics in Batch Manufacturing

Gryazin D.G., Kovalev A.S., Logovskaya E.V., CR&DI “Electropribor”, Saint-Petersburg

5.13. Structured Laser Light Bias for Technical Vision TV Systems of Mobile Robotic Complexes

Gryaznov N.A., Kirichenko V.V., CR&DI RTC, Saint-Petersburg

5.14. Telematic Tools for Measuring and Control Robotic Object Parameters

Guk M.Y., Zaborovsky V.S., CR&DI RTC, Saint-Petersburg

5.15. The choice of transducers for industrial robots experimental research

Merzlyakov A.A., Institute of Machinery, RAS, Moscow

5.16. Equipment for Radiation Spectrometry of Multifunctional Robotic Complex

Belyaev A.N., Demchenkov V.P., Kochkarev D.A., Lapin O.E., CR&DI RTC, Saint-Petersburg

5.17. Complex of Active Trilateration of Mobile Robot

Yudin A.V., MSTU n.a. N. Bauman, Moscow

5.18. Mechatronic Modules of Intersectorial Application with High Resolving Capacity

Kozyrev V.V., Vladimir State University (VSU), Vladimir

Special ISTC Session

Minor Conference Hall (room 301)

The head – professor Kondratyev A.S., Endrullat Burkhard

The secretary – professor Spassky B.A.

The technical secretary – Karpova E.G.

Tuesday, April 8

14.30-16.00 Welcoming addresses

Endrullat Burkhard, International science and technology center, Moscow

About Russian-Japanese Cooperation Under the Aegis of ISTC

Kondratiev A., Spassky B., Yudin V., CRDI RTC Russia, St-Petersburg

Kensuke Uemura, ITAC Ltd., Japan

About Russian-German Cooperation in the Field of Robotics

Kondratiev A., Spassky B., Yudin V., CRDI RTC Russia, St-Petersburg

Stephan Walther, EADS Space Transportation, Germany

Gerd Hirzinger, German Aerospace Center, Institute of Robotics and Mechatronics

Results of CRDI RTC delegation visit to Republic of Korea for participation in ISTC Workshop

Gryaznov N., Kirichenko V., CRDI RTC, St.-Petersburg

Innovation Support Project of New Technologies from Russia

Пряничников В.Е., Платонов А.К., Международная лаборатория «Сенсорика», ИПМ им.М.В.Келдыша РАН, Москва
Uglesic A., Zadar University, Croatia

An anthropomorphic gripper for service robotics

Kargov A., Gaiser I., Klosek H., Pylatiuk C., Oberle R., Werner T., Schulz S., G. Bretthauer Forschungszentrum Karlsruhe GmbH, Germany

16.00-16.30 *Coffee-break*

16.30-18.00 **Intelligent mechatronics equipments applied to measurement and integrated control processes from HIGH-TECH industrial medium**

Gheorghe I. Gheorghe, INCDMF, Bucharest, Romania

FPGA Implementation of a Non-parametric Stereo Matching Algorithm

Du Xin, Zhejiang University, P.R., China

Six DoF Sensing in Identification and Authentication for Robotics

Kvasnica Milan, Tomas Bata University in Zlin, Czech Republic

Direct Transformation of Floating Image Coordinates in 3-D Coordinate Frame in the Six-DoF Sensory System

Kvasnica Milan, Tomas Bata University in Zlin, Czech Republic

Algorithm of Inverse Transformation for the Sampling and Evaluation of Six Degrees of Freedom Information Using Floating 2-D Coordinate Frame

Kvasnica Milan, Tomas Bata University in Zlin, Czech Republic

Research and Educational problems in the format of International Eurobot Contest

Salmina M.A., MSU by M. Lomonosov, Moscow

Pavlovsky V.E., Petrovskaya N.V., M.V.Keldysh IAM RAS, Moscow

Tournois Christophe, Eurobot European Association, France

Wednesday, April 9

10.00-11.30 Smart television intruder alarm complex for Hitachi Kokusai Electric corporation (Japan)

Polovko S.A., Kogan L.B., Stepanov D.S., CR&DI RTC, Saint-Petersburg

Applications of robotic systems under extreme conditions - CHRYSOR: unmanned robotic vehicle for dangerous conditions (radiation, explosives, chemicals)

Jens Hanke, Robowatch Technologies GmbH, Berlin, Germany

Creation of new generation mobile robot

Kondratiev A., Spassky B., Polovko S., Polin A., Yudin V., CRDI RTC Russia, St-Petersburg

Stephan Walther, EADS Space Transportation, Germany

Control of flexible robots: wave-based approach

William J O'Connor, National University of Ireland

Robotic Vehicle Using Guidance System Based on Magnetic Marker

Dae-Yeong Im, Young-Jae Ryoo, Department of Control System Engineering, Mokpo National University, Republic of Korea

**Energy Foraging of Robot Swarm and Symbiotic Robot
Organism**

Paul Levi, University of Stuttgart, Germany

11.30-12.00 *Coffee-break*

Wednesday, April 9

14.30-17.30

Closing Plenary Session

Conference Hall

The Chairman – professor Yurevich E.I.

The secretary – Korsakov A.M.

1. The heads of session speak
2. Discussion
3. Conference closing