


Cogito: Plan-based Control of Robotic Agents

List of Publications

[C1] Andreas Fedrizzi, Lorenz Moesenlechner, Freek Stulp and Michael Beetz,
Transformational Planning for Mobile Manipulation based on Action-related Places,

[C2] Lorenz Mösenlechner and Michael Beetz,
Using Physics- and Sensor-based Simulation for High-fidelity Temporal Projection of Realistic Robot Behavior,
19th International Conference on Automated Planning and Scheduling (ICAPS’09)., 2009.

[C1] Michael Beetz, Freek Stulp, Bernd Radig, Jan Bandouch, Nico Blodow, Mihai Dolha, Andreas Fedrizzi, Dominik Jain, Uli Klank, Ingo Kresse, Alexis Maldonado, Zoltan Marton, Lorenz Mösenlechner, Federico Ruiz, Radu Bogdan Rusu and Moritz Tenorth,
The Assistive Kitchen – A Demonstration Scenario for Cognitive Technical Systems,
IEEE 17th International Symposium on Robot and Human Interactive Communication (RO-MAN), Muenchen, Germany, 1-8, 2008.

[C2] Lorenz Mösenlechner, Armin Müller and Michael Beetz,
High Performance Execution of Everyday Pick-and-Place Tasks by Integrating Transformation Planning and Reactive Execution,

[PhD1] Alexandra Kirsch,
Integration of Programming and Learning in a Control Language for Autonomous Robots Performing Everyday Activities,
Technische Universität München, 2008.

[PhD2] Armin Müller,
Transformational Planning for Autonomous Household Robots using Libraries of Robust and Flexible Plans,
Technische Universität München, 2008.

[C1] Michael Beetz, Jan Bandouch, Alexandra Kirsch, Alexis Maldonado, Armin Müller and Radu Bogdan Rusu,
The Assistive Kitchen — A Demonstration Scenario for Cognitive Technical Systems,
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[C2] Alexandra Kirsch and Michael Beetz,
Training on the Job — Collecting Experience with Hierarchical Hybrid Automata,

[C3] Armin Müller, Alexandra Kirsch and Michael Beetz,
Transformational Planning for Everyday Activity,

[C4] Armin Müller and Michael Beetz,
Towards a Plan Library for Household Robots,

[C1] Alexandra Kirsch and Michael Beetz,
Combining Learning and Programming for High-Performance Robot Controllers,

[C2] Alexandra Kirsch,
Towards High-performance Robot Plans with Grounded Action Models: Integrating Learning Mechanisms into Robot Control Languages,

[C3] Alexandra Kirsch, Michael Schweitzer and Michael Beetz,
Making Robot Learning Controllable: A Case Study in Robot Navigation,

[C1] Michael Beetz, Alexandra Kirsch and Armin Müller,
RPL-LEARN: Extending an Autonomous Robot Control Language to Perform Experience-based Learning,

[C2] Armin Müller, Alexandra Kirsch and Michael Beetz,
Object-oriented Model-based Extensions of Robot Control Languages,
27th German Conference on Artificial Intelligence, 2004.