Bringing geometric methods to robot learning, optimization and control

IROS 2020 Workshop

Talk title:
Planning for High-dimensional Robotic Systems by Solving Problems in Low-dimensional Manifolds

Speaker:
Maxim Likhachev
http://www.cs.cmu.edu/~maxim/

Abstract:
This talk will cover different planning methods for high-dimensional robotic systems which are built on solutions exploiting low-dimensional manifolds. Two main application problems will be explained, namely, motion planning for a 10-link robot with deformable objects and footstep/motion planning for a 30 DoF robot.