PlanRob Dagstuhl Seminar Schedule

Monday 16
9:00 - 10:00  Who’s who roundtable
Brief introduction to the organization of the seminar
Break
10:30 - 12:10  Position Statement Session 1 Long-term autonomy / Open world planning (5 talks)
Nick Hawes - Planning for long-term autonomy
Daniele Magazzeni - Strategic and Tactical Planning for Persistent Autonomy
Manuela Veloso - Persistent, Instructable, Interruptible, Transparent Autonomy
Matthias Scheutz - Planning for Open-ended Missions
Reid Simmons - Planning with Incomplete models
Lunch
13:30 - 15:10  Position Statement Session 2 Knowledge Representation and Reasoning in Planning (5 talks)
Michael Beetz - Robot Planning for the mastery of human-scale everyday manipulation tasks
Susan Epstein - Spatial Affordance for Collaborative Navigation
Lars Kunze - Explainable Robotics
Ron Petrick - Knowledge-level planning for HRI
Mak Roberts - Goal Reasoning for Robotics
Break
15:40 - 17:10  Position Statement Session 3 Challenges in Industrial, Logistics & Consumer Robotics (3 talks)
Martin Deavies - Teach Once Logistics Perspective
Amit Kumar Pandey - Some practical issues for social consumer robots: an industrial perspective
Erez Karpas - Cognitive Robotics on the Factory Floor
Break + Dinner

Tuesday 17
8:30 - 10:10  Position Statement Session 4 Human-Robot Planning (5 talks)
Rachid Alami - Towards the development of Human-aware planning abilities
Daniele Nardi - Symbiotic Human Robot Planning
Luca Iocchi - Conditional Planning for HRI
Laura Hiatt - Flexible Planning for HRI
Alberto Finzi - Flexible Execution of Human-Robot Collaborative Plans: a cognitive control approach
Break
10:30 - 12:10  Position Statement Session 5 Planning and Execution (5 talks)
Gal Kaminka - Rethinking Computational Investments in Planning and Execution
Niemueller & Lakemeyer - Towards an Integrated Approach to Planning & Execution
Joachim Hertzberg - Plan-based Robot Control
Michael Cashmore - Integrating Planning with ROS
Lenka Mudrova - Temporal Planning for Execution
Lunch
13:30 - 15:10  Position Statement Session 6 Task & Motion Planning / Hybrid planners (3 talks)
Siddarth Srivastava - On the shoulder of giants: the case of modular integration of discrete planners and continuous planners for robotics
Hector Geffner - Combined Task and Motion Planning is Classical Planning
Enrico Scala - Effective Hybrid Planners for robotics

Break
15:40 - 17:10  Position Statement Session 7 Reliable and Safe Planning for Robotics (3 talks)
Michael Hofbaur - Safety Reconsidered - planning for safe human-robot collaboration
AndreA Orlandini - How much reliable are plan-based controllers for autonomous robots?
Bruno Lacerda - Probabilistic Planning for Mobile Robots with Formal Guarantees

Break + Dinner

**Wednesday 18**
8:30 - 10:10  Position Statement Session 8 Technological Issues in Robot planning/Multi-robot Planning (5 talks)
Ronen Brafman - Plug&Play Autonomous Robots
Roman Barták - Towards Autonomous Robots via Technology Integration
Elizabeth Sklar - Data-backed Decision Making in Human-Robot Teams
Sven Koenig - Multi-Robot Planning with Spatial and Temporal Constraints
Simon Parsons - Multirobot coordination

Break
10:30 - 12:10  Miscellaneous session 1 (funding & projets)
Lunch
Hiking - Excursion

**Thursday 19**
8:30 - 10:30  Synthesis session 1
Break
11:00 - 12:10  Panel 1
Lunch
13:30 - 15:30  Synthesis session 2
Break
16:00 - 17:30  Panel 2
Break + Dinner

**Friday 20**
8:30 - 10:30  Miscellaneous session 2 (follow-up publications)
Break
11:00 - 12:10  Wrap-up and closing session
Lunch
13:00  End of the seminar