AMR 2017/18: Final Project Assignments

1. Robust gait generation for humanoids using MPC (shared with Rob 2)
Abdalla, Elhelow, Smaldone

2. CoM/ZMP estimation on the NAO humanoid (shared with Rob 2)
Cipriano, Peprah, Vianello

3. Swing-up of the cart-pendulum via learning-based MPC
Miele, Di Giammarino, Macrì

4. Lazy collision checking in sampling-based motion planning
Cansev, Ricciardi Celsi

5. Anytime asymptotically-optimal motion planning
Caruso, El Bou, Santopaolo

6. Emergency stop procedures for the HRP-4 humanoid robot
Marchitto, Trivellini, Viceconte

7. A suite of feedback controllers for unicycle robots
Di Tucci, Marroni, Perfumo