

Humanoid Robotics

Master-Seminar 2010 – Feedback

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- 1 Paper
- 2 Presentation
- 3 Grading Scheme
- 4 Questions

Each paper should use the following structure:

- Title page
 - Paper title
 - Author
 - Seminar title
 - Supervisor
 - Date or Semester
- Abstract
- Introduction
- Main sections (depending on the topic)
- Conclusion
- List of Figures (optional)
- List of Tables (optional)
- References

- Add references to copied figures
- Avoid low-resolution figures – use vector graphics
- Align figures always to the top or bottom of the page – never floating
- Provide figure labels consisting of a short description (used for the “List of Figures”) followed by a detailed description.
- Separate complex figures into panels (a, b, c, etc.) and describe each panel individually in the label

Figures - Example

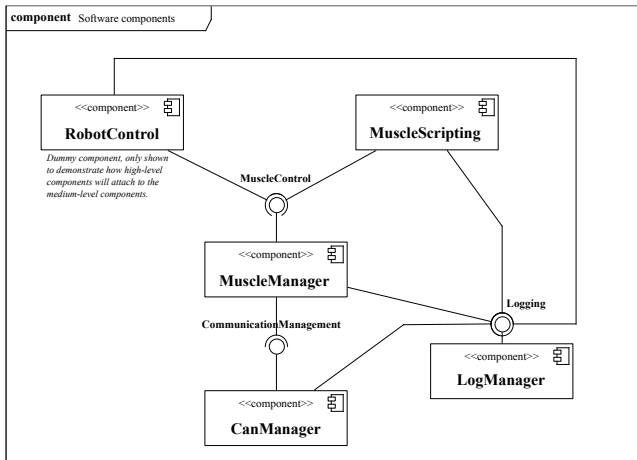


Figure: Medium-level software components. The CanManager and MuscleManager components provide the main functionality for controlling the individual muscles of the robot while the LogManager and the MuscleScripting component are used for distributed logging and system testing, respectively. The RobotControl component has been added to illustrate how high-level components will attach to the medium-level components in the future. [7]

- Prove statements using references.
- Avoid using internet sites as references (never use Wikipedia).
- Prefer high-quality references – books, dissertations, papers from high-impact journals
- Position references right after their corresponding statement
- Use standardized styles for the bibliography (e.g. DIN-1505 or \LaTeX styles)



S. Haddadin, A. Albu-Schaffer, A. De Luca, and G. Hirzinger, "Collision detection and reaction: A contribution to safe physical human-robot interaction," in *Proc. IEEE/RSJ International Conference on Intelligent Robots and Systems IROS 2008*, 2008, pp. 3356–3363



O. Holland and R. Knight, "The anthropomorphic principle," in *Adaptation in Artificial and Biological Systems*, 2006



I. Mizuuchi, T. Yoshikai, Y. Sodeyama, Y. Nakanishi, A. Miyadera, T. Yamamoto, T. Niemela, M. Hayashi, J. Urata, Y. Namiki, T. Nishino, and M. Inaba, "Development of musculoskeletal humanoid kotaro," in *Proc. IEEE International Conference on Robotics and Automation ICRA 2006*, 2006, pp. 82–87



H. Kino, S. Kikuchi, T. Yahiro, and K. Tahara, "Basic study of biarticular muscle's effect on muscular internal force control based on physiological hypotheses," in *Proc. IEEE International Conference on Robotics and Automation ICRA '09*, 2009, pp. 4195–4200



E. R. Kandel, J. H. Schwartz, and T. M. Jessel, *Principles of Neural Science*, 4th ed., J. Butler and H. Lebowitz, Eds. McGraw-Hill, 2000

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- try to use graphics
- do not just put your headwords on the slides
- don't put longer text on your slides, nobody will read it

Correct translation ;-)

Actuator \neq Aktuator

Actuator = Akteur

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Grading Scheme

The following grading scheme was used:

Presentation	Paper	Commitment
Content (15 %)	Content (10 %)	Presentation contributions (10 %)
Slide style (5 %)	Structure/Layout/Figures (10 %)	Reference Quality (8 %)
Replies to questions (10 %)	Examples (5 %)	Independence (8 %)
Presentation style (10 %)	Referencing (4 %)	
Time management (5 %)		
45 %	29 %	26 %

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Any questions?