

Bloc horaire	Présentateur	Titre de l'article	CONFIRMÉ
8h30-10h20	Clément Le Naour	A direct visual servoing-based framework for the 2016 IROS Autonomous Drone Racing Challenge	
	Antoine Guay	A modular framework for model-based visual tracking using edge, texture and depth features	
	Edin Kolar	A Combined RGB and Depth Descriptor for SLAM with Humanoids	
	Cedric Aitkadi	Real-Time Monocular Object-Model Aware Sparse SLAM	
	Baptiste Perceval Pornin	Multi-Hierarchical Semantic Maps for Mobile Robotics	
	Israel Akobi	A Behavioral Approach to Visual Navigation with Graph Localization Networks	
10h30-12h20	Mark Chalet	GPS/IMU data fusion using multisensor Kalman filtering: introduction of contextual aspects	y
	Philippe Trépanier	Unsupervised Learning for Solving RSS Hardware Variance Problem in WiFi Localization	
	Ruoyu Liu	ORB-SLAM: a Versatile and Accurate Monocular SLAM System	
	Adjété Fred Wilson-Bahun	Dynamic Perimeter Surveillance with a Team of Robots	
	Nantenaina Rabemifara Mamiharimala	Crowd-Robot Interaction: Crowd-aware Robot Navigation with Attention-based Deep Reinforcement Learning	
	Antoide Bardiaux	M-Blocks: Momentum-driven, Magnetic Modular Robots	y
12h30-14h20	William Guimont-Martin	Matching with PROSAC – Progressive Sample Consensus	
	Vincent Grondin	Tree Cavity Inspection using Aerial Robot	y
	Dominic Baril	estimation kalman skid steering	y
	Bruno Kinder Almentero	LOAM	
	Afaf Derraf	MIM_SLAM: A Multi-Level ICP Matching Method for Mobile Robot in Large-Scale and Sparse Scenes	