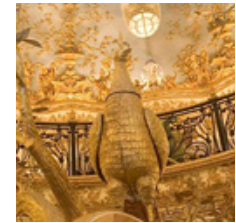




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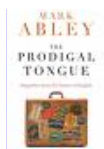
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That makes it easier to show children how the movie relates to science in the real **world**, Fink says. "**Robots** will be the next big thing to come," Fink said. ...[DIS](#)

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RC Arkin - Designing Autonomous Agents: Theory and Practice From ..., 1990 - books.google.com

... constructed under these conditions, a **robot could** use this ... sch?mas success- fully completing the **robot's** mission. ... maintain-al- titude with **other** sch?mas such ...

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... As a result, the **robot could** waste a great deal of ... rangefinders commonly found on mobile **robots** are limited ... reading is independent of every **other** sensor reading ...

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MJ Mataric, M Nilsson, K Simsarian - ... 1995 IEEE/RSJ International Conference on Intelligent **Robots** ..., 1995 - doi.ieeecomputersociety.org

... The **other** is to handle the communication with **other robots** to which one of the ... here, we used a 5-meter cable between the **robots** that **could** easily transmit ...

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IM Rekleitis, G Dudek, E Milios - Proc. of the International Joint Conference on Artificial ..., 1997 - users.cs.dal.ca

... are a vision system that **could** locate a ... finder with a retroreflective target on the **other robot**. ... The **robots explore** the unknown environment by pro- gressively ...

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I Rekleitis, G Dudek, E Milios - Annals of Mathematics and Artificial Intelligence, 2001 - Springer

... The first approaches centered on the exploration of an unknown **world** using a single sensor such as ... The fact that two **robots could** see each **other** was not ...

[Integrating Exploration and Localization for Mobile Robots -](#)

B Yamauchi, A Schultz, W Adams - Adaptive Behavior, 1999 - adb.sagepub.com

... A mobile **robot** needs to **explore** in order to learn the spatial structure of the **world**, and to incorporate this structure into some form of map. ...

[Delivering real reality to the World Wide Web via telerobotics -](#)

E Paulos, J Canny - Robotics and Automation, 1996. Proceedings., 1996 IEEE ..., 1996 - ieeexplore.ieee.org

... and to comments left by **other** users. ... fixed cameras in re- mote spaces where users **could** observe dynamic ... of free- dom was realized by introducing **robots** to the ...

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MJ Mataric - Proceedings of the Eleventh International Conference on ..., 1994 - cwis.usc.edu

... In the mean time it **could** be repeatedly interrupted by **other** activities, such as ... the correct mapping was dicult to learn since the **robots** did not ...

[On autonomous robots -](#)

GA BEKEY - The Knowledge Engineering Review, 2001 - Cambridge Univ Press

... It **could** read sheet music, and control its arms ... future the boundary between softbots and **robots** may become ... experience, and to interact with each **other** and with ...

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Mars Rover

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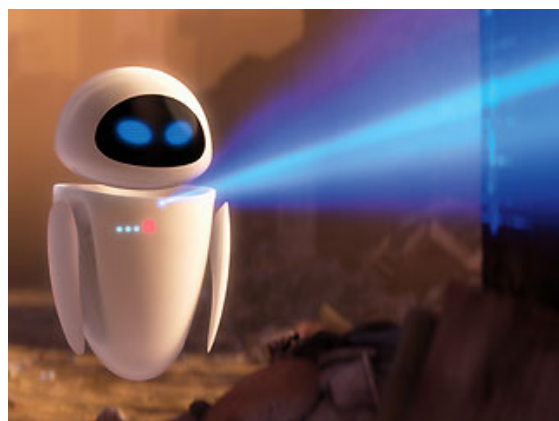
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Pixar/Disney

EVE, otherwise known as the Extra-terrestrial Vegetation Evaluator, represents an intelligent probe sent to an abandoned Earth in the film 'WALL-E.'

EVE, otherwise known as the Extra-terrestrial Vegetation Evaluator, represents an intelligent probe sent to an abandoned Earth in the film 'WALL-E.'

A spaceship descends with a thunderous roar and deposits a futuristic probe before taking off again. The Extraterrestrial Vegetation Evaluator (EVE) soon activates and begins flying around, scanning the barren surface for signs of life.

Scientists today can only dream of having a robotic explorer like EVE from the Disney/Pixar film "WALL•E."

But some researchers are working on autonomous spacecraft, airships and rovers that can cooperate intelligently while exploring distant worlds.

"The orbiter gives you global perspective, the aerial platform a more regional perspective, and that helps determine where to deploy ground assets in a targeted fashion," said Wolfgang Fink, a physicist at the California Institute of Technology in Pasadena.

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Fink's vision of "tier-scalable reconnaissance" starts with an orbiting spacecraft to make a global survey for interesting scientific targets, before deciding on its own where to deploy an airship such as a dirigible.

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The airship could look even closer at a region to find the best landing site, and finally drop a rover or some other surface explorer. That surface explorer could then move quickly to the target area.

A demonstration of how such a surface explorer might deploy will take place in the Mars Science Laboratory mission, slated for a 2009 launch.

NASA's Sky Crane carrier will hover above the surface of Mars on retrorockets while lowering an SUV-sized rover using a winch and tether.

Some Mars missions have already demonstrated the advantage of coordinating orbiters with surface explorers.

Scientists used data from three Mars orbiters to determine the landing site for NASA's Phoenix Mars Lander, and also turned orbiter cameras on the lander as it descended to the surface.

Of the three orbiters, the Mars Reconnaissance Orbiter has even helped NASA's separate Spirit and Opportunity Rovers navigate around obstacles on the Martian surface.

However, Fink and his collaborators want to take humans out of the loop and develop robots which can decide independently when and where to go.

That becomes crucial for future missions to distant places such as the moons of Saturn or Jupiter, where a command signal from Earth can take over an hour to reach robotic explorers.

The key rests with software algorithms that help robots make command decisions on their own.

Fink's group has begun testing such algorithms by using three small rovers and a camera that looks down on a simulated indoor landscape.

The camera identifies both targets and obstacles, which allows the rovers to deploy and drive around obstacles to reach their targets — all without human intervention.

"Integration is the biggest challenge," Fink noted. "At Caltech, we are now at the point where we're implementing a test-bed outdoors to develop the software to demonstrate this in action."

The outdoors test would involve a miniature airship taking the place of the camera. Researchers from around the world would be able to give commands to the airship via Internet and watch it move and deploy the rovers on its own.

The field tests may pave the way for using similar command software on the proposed NASA and European mission to Titan or Europa. Fink and other researchers involved with the planning have begun discussing how such a mission might shape up by the 2017 launch date.

"A Titan mission would have the orbiter deploying a balloon, and we're already thinking about having a lander," Fink explained. "There you have a three-tier mission."

The tiered approach may eventually take the form of a robot that "does its own reconnaissance, goes out and looks for anomalies, finds something interesting and makes contact with the sender," Fink said, pointing to the Imperial probe from "The Empire Strikes Back" which lands on the ice planet Hoth.

Perhaps best of all, intelligent robots could react quickly to surprises and investigate anomalies — such as a geyser on Saturn's moon Enceladus, or a landslide on Mars.

"Curiosity in itself is not present in any of our machine systems," Fink said, remarking upon WALL•E's childlike tendencies which appear to distract EVE but eventually help her mission. "That curiosity drives action."

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