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003	R. Jarvis	Ray.Jarvis@eng.monash.edu.au	A Go Where you Look Tele-Autonomous Rough Terrain Mobile Robot
005	A. Martinoli, K. Easton	alcherio@micro.caltech.edu	Reality and Abstraction in Distributed Robotic Systems
006	D. Beymer, K. Konolige	konolige@ai.sri.com	Tracking People from a Mobile Platform
007	K.J. Waldron, K. Tollon	waldron@cdr.stanford.edu	Mechanical Characterization of the Immersion Corp. Haptic, Bimanual, Surgical Simulator Interface
008	T. Yoshikawa, M. Kawai, K. Yoshimoto	yoshi@mech.kyoto-u.ac.jp	Toward Observation of Human Assembly Skill Using Virtual Task Space
009	C. Azevedo, N. Andreff, S. Arias, B. Espiau	Nicolas.Andreff@ifma.fr	Experimental BIPedal walking
010	G. Ferretti, G. Magnani, G. Martucci, P. Rocco, V. Stampacchia	GianAntonio.Magnani@Elet.PoliMi.IT	Friction Model Validation in Sliding and Pre-sliding Regimes with High Resolution Encoders
014	V. Gavrilets, B. Mettler, I. Martinos, E. Feron	gavrick@MIT.EDU	Control and Guidance for Aggressive Maneuvering of a Miniature Helicopter
015	S. Saripalli, G.S. Sukhatme, J.F. Montgomery	gaurav@pollux.usc.edu	An Experimental Study of the Autonomous Helicopter Landing Problem
019	A. Kawakami, A. Torii, K. Motomura, S. Hirose	kawakami@mes.titech.ac.jp	SMC Rover: Planetary Rover with transformable wheels
020	N. Apostoloff, L. Fletcher, A. Zelinsky	nema@syseng.anu.edu.au	Vision In and Out of Vehicles: Integrated Driver and Road Scene Monitoring
022	S. Sukkarieh	salah@acfr.usyd.edu.au	Decentralised Coordinated Control for Autonomous Robot Systems
023	M. Kaneko, R. Takenaka, M. Ishikawa	kaneko@huis.hiroshima-u.ac.jp	The Capturing Robot with Super High Acceleration
024	E. Nebot, F. Masson, J. Guivant, H. Durrant-Whyte	nebot@acfr.usyd.edu.au	Robust Simultaneous Localization and Map Building Algorithms for Very Large Outdoor Environments
026	K. Yokoi, F. Kanehiro, K. Kaneko, K. Fujiwara, S. Kajita, H. Hirukawa	Kazuhito.Yokoi@aist.go.jp	Experimental Study of Biped Locomotion of Humanoid Robot HRP-1S
028	R. Bischoff, V. Graefe	Graefe@UniBw-Muenchen.de	Dependability as Design Goal of Future Service Robots
029	A. De Luca, V. Caiano, D. Del Vescovo	deluca@dis.uniroma1.it	Experiments on Rest-to-Rest Motion of a Flexible Arm
030	G. Duchemin, E. Dombre, F. Pierrot, Ph. Poignet	duchemin@lirmm.fr	Robotized Skin Harvesting
031	C. Laugier, C. A. Mendoza, K. Sundaraj	Christian.Laugier@inrialpes.fr	Faithfull Haptic Feedback in Medical Simulators

032	K. Nishiwaki, S. Kagami, J.J. Kuffiner, K. Okada, Y. Kuniyoshi, M. Inaba, H. Inoue	s.kagami@aist.go.jp	Online Humanoid Locomotion Control by Using 3D Vision Information
035	W.R. Provancher, M.R. Cutkosky	wil@cdr.stanford.edu	Sensing Local Geometry for Dexterous Manipulation
037	J. Amat, A. Casals, M. Frigola, E. Martín	casals@esaii.upc.es	Experimental Bilateral Control Telemanipulation Using a Virtual Exoskeleton
038	K. Yoshida, H. Hamano, T. Watanabe	yoshida@astro.mech.tohoku.ac.jp	Slip-Based Traction Control of a Planetary Rover
039	A. Howard, M.J. Mataric	mataric@pollux.usc.edu	Localization for Mobile Robot Teams: A Distributed MLE Approach
040	T. Debus, P. Dupont, R.D. Howe	pierre@bu.edu	Contact State and Property Estimation using Multiple Model Estimation and Hidden Markov Models
041	B. Hannaford, J.-H. Ryu, D.-S. Kwon, Y.S. Kim, J.-B. Song	blake@kant.ee.washington.edu	Testing Time Domain Passivity Control of Haptic Enabled Systems
043	Y. Zhang, K. Roufas, C. Eldershaw, M. Yim, D. Duff	yzhang@parc.xerox.com	Sensor Computations in Modular Self Reconfigurable Robots
044	N. Vandapel, M. Hebert	vandapel@cs.cmu.edu	3D Rover Localizationin Airborne Ladar Data
045	E. Altug, J. Ostrowski, C.J. Taylor	erdinc@grasp.cis.upenn.edu	Quadrotor Control Using Dual Camera Visual Feedback
046	J.E. Lloyd, D.K. Pai	lloyd@cs.ubc.ca	Interactive Exploration of Remote Objects Using a Haptic-VR Interface
047	G. Buskey, J. Roberts, P. Corke, G. Wyeth, P. Ridley	pic@cat.csiro.au	The CSIRO Autonomous Helicopter Project
050	D.C. Conner, P.N. Atkar, A.A. Rizzi, H. Choset	arizzi@ri.cmu.edu	Experimental Verification of Deposition Models for Automotive Painting with Electrostatic Rotating Bell Atomizers
051	S. Thrun, R. Biswas, B. Limketkai, S. Sanner	thrun@Stanford.EDU	Tracking and Mapping Slow-Moving Objects in Dynamic Environments
053	S. Lacroix, I.-K. Jung, P. Soueres, E. Hygounenc, J.-P. Berry	Simon.Lacroix@laas.fr	The Autonomous Blimp Project of LAAS/CNRS Current Status and Research Challenges
055	N. Koizumi, T. Kato, S. Warisawa, H. Hashizume, M. Mitsuishi	mamoru@nml.t.u-tokyo.ac.jp	Manipulability Enhancement by an Impedance Parameter Tuning for a Remote Ultrasound Diagnostic System

056	G.A.S. Pereira, J. Spletzer, V. Kumar, C.J. Taylor and M.F.M. Campos	guilherm@grasp.cis.upenn.edu	Cooperative Transport of Planar Objects by Multiple Mobile Robots Using Object Closure
057	D. Yi, V. Hayward	hayward@cim.mcgill.ca	A New Approach to the Haptic Display of Surface Shape and Texture
060	J. Swevers, B. Naumer, S. Pieters, E. Biber, W. Verdonck	jan.swevers@mech.kuleuven.ac.be	An Experimental Robot Load Identification Method for Industrial Application
061	K. Iagnemma, M. Spenko, D. Golda, S. Dubowsky	kdi@MIT.EDU	Experimental Study of Vehicle and Terrain Models for High-Speed Rough-Terrain Mobile Robots
062	S. Singh, G. Kantor, D. Strelow	ssingh@ri.cmu.edu	Recent Results in Extensions to Simultaneous Localization and Mapping
064	R. Siegwart, K.O. Arras, N. Tomatis	kai-oliver.arras@epfl.ch	Robox, A Remarkable Mobile Robot For The Real World
065	D.S. Haliyo, S. Regnier, P. Bidaud	philippe@robot.uvsq.fr	Manipulation of Micro-Objects Using Adhesion Forces and Dynamical Effects
067	G. Chrikjian	gregc@jhu.edu	Toward Self-Replicating Robots
072	L. Adhami, E. Coste-Manière, F. Mourgues, O. Bantiche, J. Ruurda, I. Broeders, C. Coirier, A. Lobontiu, A. Carpentier	ladhami@sophia.inria.fr	Optimal Planning of Robotically Assisted Heart Surgery: Transfer Precision in the Operating Room
073	Z. Butler, R. Fitch, D. Rus	zackb@hummingbird.cs.dartmouth.edu	Experiments in Distributed Control for Modular Robots
076	A. Krupa, C. Doignon, J. Gangloff, M. de Mathelin, G. Morel, L. Soler, J. Leroy, J. Marescaux, M. Ghodoussi	morel@robot.uvsq.fr	Towards Semi-Autonomy in Laparoscopic Surgery: First Live Experiments
077	J.P. Barreto, F. Martin, R. Horaud	Joao.Barreto@inrialpes.fr	Visual Servoing Using Central Catadioptric Images
079	T. Inamura, I. Toshima, Y. Nakamura	inamura@ynl.t.u-tokyo.ac.jp	Acquiring Motion Elements for Bidirectional Computation of Motion Recognition and Generation
083	R. Cupec, G. Schmidt	robert.cupec@ei.tum.de	Practical Experience with Vision-Based Biped Walking
084	P. Murrieri, D. Fontanelli, A. Bicchi	bicchi@ing.unipi.it	Visual-Servoed Parking with a Limited View Angle
085	S. Yu, M.A.Greminger, D.P.Potasek, B.J.Nelson	nelson@me.umn.edu	A Visually Servoed Multi-Axis MEMS Manipulator
086	G.R. Dunlop	r.dunlop@canterbury.ac.nz	Foot Design for a Large Walking Delta Robot

087	D. Campbell, J.-P. Granger, M. Buehler	buehler@cim.mcgill.ca	Preliminary Bounding Experiments in a Dynamic Hexapod
088	M. Gienger, K. Loffler, F. Pfeiffer	gienger@amm.mw.tu-muenchen.de	Practical Aspects of Biped Locomotion
089	T. Tsubouchi, T. Yamaguchi, S. Yuta	tsubo@roboken.esys.tsukuba.ac.jp	Online Sensor-based Behavior Decision and Navigation of a Mobile Robot in Unknown Indoor Environment
091	M. Zinn, O. Khatib, B. Roth, J.K. Salisbury	zinn@Robotics.Stanford.EDU	A New Actuation Approach for Human Friendly Robot Design
092	P. Dario, P. Ciarletta, A. Menciassi, B. Kim	arianna@sssup.it	Modeling and Experimental Validation of the Locomotion of Endoscopic Robots in the Colon
094	M.R. Sirouspur, S.E. Salcudean	tims@ece.ubc.ca	Robust Controller Design for Cancelling Biodynamic Feedthrough
095	D. Meeker, S. Cao, K.V. Shenoy, R.A. Andersen, J.W. Burdick	jwb@robby.caltech.edu	Moving by Thinking: Progress Toward a Cortical Neural Prosthesis for Robotics Arms