

EECS Seminar



Title: Introduction of Aldebaran Robotics and A Demonstration of Nao Robot Using Chorégraphie

Speaker: Dr. Natanel Dukan

Host: Dr. Lingfeng Wang

Abstract: Nao is a humanoid robot developed and manufactured by Adebaran Robotics, a French company based in Paris, France. The demonstration will show how the robot interact and the capacities of high level programming through software.

Nao stands tall in all points amongst its robotic brethren. Platform agnostic, it can be programmed and controlled using Linux, Windows or Mac OS. The hardware has been built from the ground up with the latest technologies providing great fluidity in its movements and offering a wide range of sensors. Nao contains an open framework which allows distributed software modules to interact together seamlessly. Depending on the user's expertise, Nao can be controlled via Choregraphie®, our user friendly behaviour editor, by programming C++ modules, or by interacting with a rich API from scripting languages.

In addition to the high level API, advanced users can take advantage of low level access to sensors and actuators and can, if they wish, replace our code with custom adaptations. In order to allow users to validate motion sequences, simulators are available for Microsoft Robotics Studio and Webots.

Company profile

ALDEBARAN ROBOTICS was founded in 2005 in Paris to develop and market humanoid home robot companions. Since May 2008, Aldebaran is shipping its first generation robot. Nao is a 58cm tall friendly robot that includes a computer and networking capability at its core. Delivered with a full set of development tools, NAO addresses the needs of universities including RoboCup players and research labs around the world. It's an evolving platform, which is unique in its ability to handle multiple applications. Today Aldebaran's regroups more than 70 people including +35 first class engineers and PhDs involved in R&D and production.

Date: November 9, 2009 (Monday)

Time: 2:00—3:00 p.m.

Location: EECS Conference Room (NI 2004)



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