RoboCup Symposium 2023 - Program 43 rue Pierre Noailles, Domaine du Haut Carré 33400 Talence

July 10, 2023

	Туре	Name(s)	Title
8:45 - 9:00	Welcome	Cédric Buche, Alessandra Rossi, Marco Simoes, Ubbo Visser	Greetings, statistics and best paper candidates
			Social Robots: Reflections and Predictions of Our Future Relationship with
9:00 - 10:00	Keynote 1	Cynthia BREAZEAL	Personal Robots
10:00 - 10:30	Oral Session	Leonardo da Silva Costa and Flavio Tonidandel	Multi-Robot Path Planning with Safety Based Control applied to the Small Size League Robots
10:30 - 11:00		Poster Se:	ssion 1, regular papers + Coffee break
11:00 - 11:30	Oral Session	Katarzyna Pasternak, Christopher Duarte, Julio Ojalvo, Ubbo Visser and Christine Lisetti	3D Multimodal Socially Interactive Robot with ChatGPT Active Listening
11:30 - 12:00	Oral Session	Sinuo Wang, Maëlic Neau and Cédric Buche	RoboNLU: Advancing Command Understanding with a Novel Lightweight BERT- based Approach for Service Robotics
12:00 - 13:00			Lunch Break
12.00			
13:00 - 14:00	Keynote 2	Laurence DEVILLERS	тва
14:00 - 14:30	Oral Session	Jacques Saraydaryan, Jumel Fabrice and Olivier Simonin	Human Presence Probability Map (HPP): a Probability propagation based on Human Flow Grid
14:30 - 15:00	Oral Session		
		Diana Kleingarn and Dominik Brämer	Neural Network and Prior Knowledge Ensemble for Whistle Recognition
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15:00 - 15:30		-	Neural Network and Prior Knowledge Ensemble for Whistle Recognition Session 2, dev papers + Coffee break
	Keynote 3	Poster S	Session 2, dev papers + Coffee break
15:00 - 15:30 15:30 - 16:30	Keynote 3	-	
	Keynote 3 Oral Session	Poster S	Session 2, dev papers + Coffee break
15:30 - 16:30 16:30 - 17:00	Oral Session	Poster S DeepMind Vincenzo Suriani, Emanuele Musumeci, Daniele Nardi and Domenico Daniele Bloisi	TBA Play Everywhere: A Temporal Logic based Game Environment Independent Approach for Playing Soccer with Robots
15:30 - 16:30		Poster S DeepMind Vincenzo Suriani, Emanuele Musumeci, Daniele Nardi and	TBA Play Everywhere: A Temporal Logic based Game Environment Independent Approach
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