Publications techniques[1]

Moëz Cherif [2]

Articles dans des journaux internationaux

>[1] **M. Cherif**, "Motion Planning for All-Terrain Vehicles: A Physical Modeling Approach for Coping with Dynamic and Contact Interaction Constraints", **IEEE Transactions on Robotics and Automation**, vol. 15, no. 2, pages 202–218, avril 1999 (papier régulier).

[2] **M. Cherif** and K. K. Gupta, "Planning Quasi-static Fingertip Manipulations for Re-configuring Objects", **IEEE Transactions on Robotics and Automation**, vol 15, no. 5, pages 837–848, octobre 1999 (papier régulier). (*Paru comme Rapport de Recherche CSS-IS TR 96-05, Simon Fraser University, Canada, novembre 1996.*)

[3] **M. Cherif** and K. K. Gupta, "A Global Planner for In-Hand Dextrous Re-Configuration of Rigid Objects", **International Journal of Advanced Robotics**, vol. 13, no. 4, décembre 1999 (papier régulier). *(Sélectionné par le comité de programme de la conférence IEEE/RSJ IROS pour la "Special Issue IROS'98".)*

[4] **M. Cherif**, M. Vidal, and Ch. Laugier, "A Roadmap-based Algorithm for Planning Handling Operations in Changing Industrial Plants", **International Journal of Robotics and Automation**, papier régulier à paraître (accepté en décembre 1999). (*Paru comme Rapport de Recherche INRIA RR-3629, février 1999.*)

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[5] **M. Cherif** and K. K. Gupta, "Global Planning for Dextrous Re-orientation of Rigid Objects: Finger Tracking with Rolling and Sliding", **International Journal of Robotics Research**, papier régulier en cours de "review" (soumis en juin 1999, **conditionnellement accepté**). (*Paru comme Rapport de Recherche INRIA RR-3770, septembre 1999.*)

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[4] **M. Cherif** and K. K. Gupta, "Planning for In-Hand Dextrous Manipulation", P Agarwal, L. Kavraki, and M. Mason (Eds), **Robotics, the Algorithmic Perspective**, pages 103–117, A.K. Peters Publisher, Wellesley (MA), USA, 1998.

>[3] **M. Cherif**, "Physical Models for Solving Off-Road Vehicle Motion Planning", J. Rix, S. Haas, and J. Teixeira (Eds), **Virtual Prototyping - Virtual Environments and the Product Design Process**, pages 261–270, IFIP, Chapman & Hall, Londres, Royaume-Uni, 1995.

[2] Ch. Laugier, Ch. Bard, **M. Cherif**, and A. Joukhadar, "Solving Complex Motion Planning Problems by Combining Geometric and Physical Models: The Cases of a Rover and of a Dextrous Hand", K. Goldberg, D. Halperin, J-C. Latombe, and R. Wilson (Eds), **Algorithmic Foundations of Robotics**, pages 185–201, A.K. Peters Publisher, Wellesley (MA), USA, 1995.

[1] **M. Cherif**, Ch. Laugier, Ch. Milési-Bellier, and B. Faverjon, "Combining Physical and Geometric Models to Plan Safe and Executable Motions for a Rover Moving on a Terrain", T. Yoshikawa and F. Miyazaki (Eds), **EXPERIMENTAL ROBOTICS III**, Lecture Notes in Control and Information Sciences, Springer-Verlag, Vol. 200, pages 456–475, octobre, 1994.

[1] Liste établie au 05.01.2000. Les numéros précédés du signe > corrrespondent à des publications à auteur unique.

[2] Ingénieur expert, Projet VASY, INRIA Rhône-Alpes, 655 avenue de l'Europe, 38331, Montbonnot St-Martin, France. (E-mail: `Moez.Cherif@inrialpes.fr`.)

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[17] **M. Cherif**, J. Ibañez-Guzmán, T. Goh and Ch. Laugier, "Motion Planning for an All-Terrain Autonomous Vehicle", **Int. Conf. on Field and Service Robotics**, pages 104–109, Carnegie Mellon University, Pittsburgh, PA, USA, août, 1999.

>[16] **M. Cherif**, "Kinodynamic Motion Planning for All-Terrain Wheeled Vehicles", **IEEE Int. Conf. on Robotics and Automation (ICRA)**, Detroit, Michigan, USA, mai, 1999.

[15] **M. Cherif** and K. K. Gupta, "3D In-Hand Manipulation Planning", **IEEE Int. Conf. on Intelligent Robots and Systems (IROS)**, pages 146–151, Victoria, B.C., Canada, octobre, 1998.

[14] **M. Cherif** and M. Vidal, "Planning Handling Operations in Changing Industrial Plants", **IEEE Int. Conf. on Robotics and Automation (ICRA)**, pages 881–886, Louvain, Belgique, mai, 1998.

[13] **M. Cherif** and K. K. Gupta, "Towards Practical Global Motion Planning for In-Hand Manipulation of 3D Objects", **IEEE System, Man and Cybernetics Int. Multi-Conf. on Computational Engineering in Systems Applications (CESA)**, Nabeul-Hammamet, Tunisie, avril, 1998.

[12] **M. Cherif** and K. K. Gupta, "Planning for In-Hand Dextrous Manipulation", Preprints of **Third Workshop on the Algorithmic Foundations of Robotics (WAFR)**, Houston, Texas, USA, mars 5-7, 1998.

[11] **M. Cherif** and K. K. Gupta, "Practical Motion Planning for Dextrous Re-orientation of Polyhedra", **IEEE/RSJ Int. Conf. on Intelligent Robots and Systems (IROS)**, pages 291–297, Grenoble, France, septembre, 1997.

[10] **M. Cherif** and K. K. Gupta, "Planning Quasi-static Motions for Re-configuring Objects with a Multi-fingered Robotic Hand", **1997 IEEE Int. Conf. on Robotics and Automation (ICRA)**, pages 986–991, Albuquerque, New Mexico, USA, avril, 1997.

>[9] **M. Cherif**, "On All-Terrain Vehicle Motion Planning", **Third Int. Symposium on Intelligent Robotic Systems (ISIRS)**, pages 91–95, Pise, Italie, juillet, 1995.

[8] **M. Cherif** and Ch. Laugier, "Motion Planning of Autonomous Off-Road Vehicles Under Physical Interaction Constraints", **IEEE Int. Conf. on Robotics and Automation (ICRA)**, pages 1687–1693, Nagoya, Japon, mai, 1995. (*paru comme Rapport de Recherche RR-2370, INRIA, France, octobre, 1994, auteur: M. Cherif.*)

[7] **M. Cherif** and Ch. Laugier, "On Physically-based Modeling and Off-Road Vehicle Motion Planning", **Int. Conf. on Intelligent Autonomous Systems (IAS-4)**, pages 482–489, IOS Press, Karlsruhe, Allemagne, mars, 1995.

>[6] **M. Cherif**, "Coping with Robot/Environment Interactions for Solving Off-Road Vehicle Motion Planning", **IFIP TC 5 WG 5.10 Workshop on Virtual Environment**, Coimbra, Portugal, octobre, 1994.

[5] **M. Cherif** and Ch. Laugier, "Dealing with Vehicle/Terrain Interactions when Planning the Motions of a Rover", **IEEE/RSJ/GI Int. Conf. on Intelligent Robot and Systems (IROS)**, pages 579–586, Munich, Allemagne, septembre 1994.

[4] **M. Cherif**, Ch. Laugier, Ch. Milési-Bellier, and B. Faverjon, "Planning the Motions of an All-Terrain Vehicle by Using Geometric and Physical Models", **IEEE Int. Conf. on Robotics and Automation (ICRA)**, pages 2050–2056, San Diego, USA, May 1994.

[3] Ch. Laugier, Ch. Bard, **M. Cherif**, and A. Joukhadar, "Solving Complex Motion Planning Problems by Combining Geometric and Physical Models: The Cases of a Rover and of a Dextrous Hand", Preprints of **First Workshop on the Algorithmic Foundations of Robotics (WAFR)**, San Francisco, USA, février, 1994.

[2] **M. Cherif**, Ch. Laugier, Ch. Milési-Bellier, and B. Faverjon, "Combining Physical and Geometric Models to Plan Safe and Executable Motions for a Rover Moving on a Terrain", Preprints of **Third Int. Symposium on Experimental Robotics (ISER)**, pages 22–30, Kyoto, Japon, octobre, 1993.

[1] **M. Cherif** and Ch. Laugier, "Using Physical Models to Plan Safe and Executable Motions for a Rover Moving on a Terrain", **First Int. Workshop on Intelligent Robotic Systems (IRS)**, pages 57–66. J.L.Crowley and A. Dubrowsky (Eds), Zakopane, Pologne, juillet, 1993.

Rapports de recherche

Total : 4 rapports de recherche (1 RR Simon Fraser University, Canada, et 3 RR INRIA, France).

Voir [2], [4], et [5] dans la rubrique "Journaux internationaux", et [8] dans la rubrique "Conférences internationales", (NB. [8] est apparu comme RR INRIA avec comme seul auteur M. Cherif.)

Thèses (Doctorat et D.E.A.)

[1] **M. Cherif**, "Planification de mouvements pour un robot mobile autonome tout-terrain : une approche par utilisation des modèles physiques", Thèse en Informatique de l'Institut National Polytechnique de Grenoble (INPG), 135 pages, Grenoble, France, octobre 1995. (Directeur de thèse: Dr. Christian Laugier, DR INRIA).

[2] **M. Cherif**, "Algorithmes de détermination fonctionnelle d'entrées de test de microprocessors", Mémoire de DEA en Informatique, ENSIMAG-INPG, Grenoble, France, juin 1991. (Directeur de stage: Dr. Bernard Courtois, DR CNRS).