



文献检索

外文全文数据库的检索与利用

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- 5 哈工大外文全文数据库

ACS 美国化学学会



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1.2 英文检索式的制定

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切分：~~基于~~~~高速~~~~视觉~~~~的~~~~管道~~~~巡检~~~~机器人~~~~的~~~~研究~~

增删：

图像处理、
图像识别

管

检测、
探测

机器人、
机械装置

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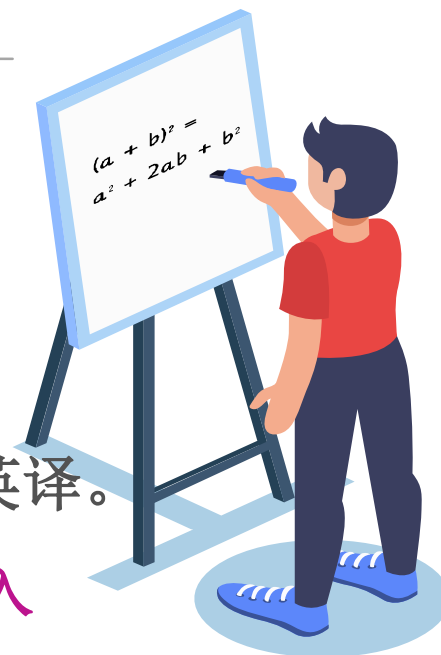
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检索式： (机器人 or 机械装置) and (管道 or 管) and (视觉 or 图像) and (探测 or 检测)

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1. 利用有道翻译、百度翻译、知网翻译对检索词进行英译。
2. 不确定的字母可以使用通配符“?”来查询，如键入“visu?l”可找到“visual”、“visuel”。
3. 活用截词符，在关键词后面加上“*”可以找到不同意义的字，如键入“pipe*”可以找到“pipe”、“pipeline”。



1.2 英文检索式的制定

课题：基于高速视觉的管道巡检机器人的研究

4.短语检索（“”）用于检索固定短语。

5.运用位置算符，“Nn”和“Wn”表示两个检索词之间的位置邻近关系。

Nn: 两个检索词相隔距离最多为n个单词，两词出现的顺序可互换。

Wn: 两个检索词相隔距离最多为n个单词，两词出现的顺序不可互换。

6.布尔逻辑算符两边需要空格，采用英文半角括号来改变优先级。



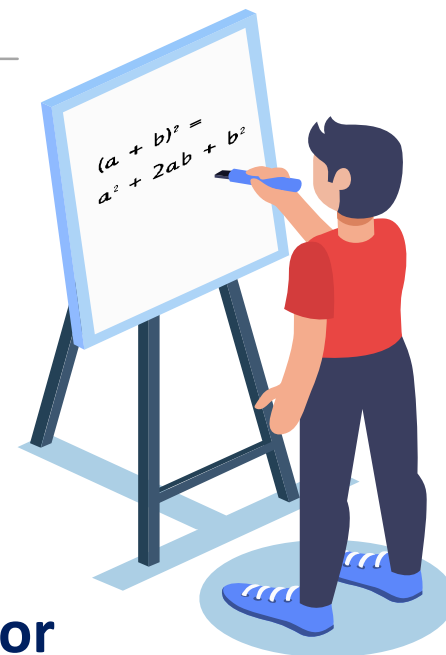
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(探测 or 检测)

构建英文检索式：

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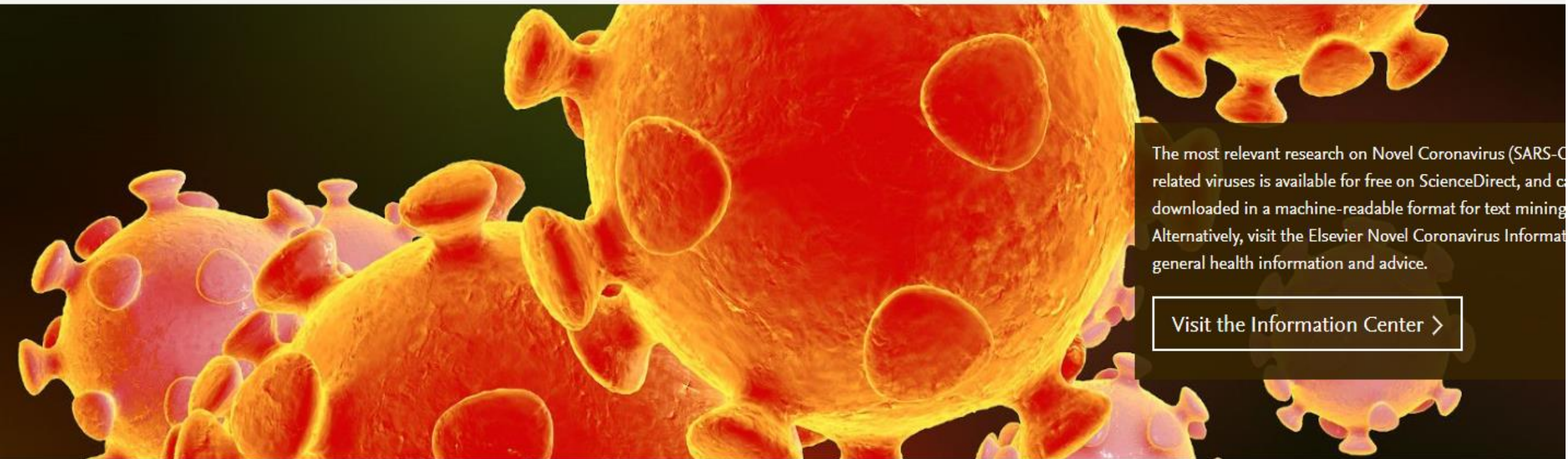
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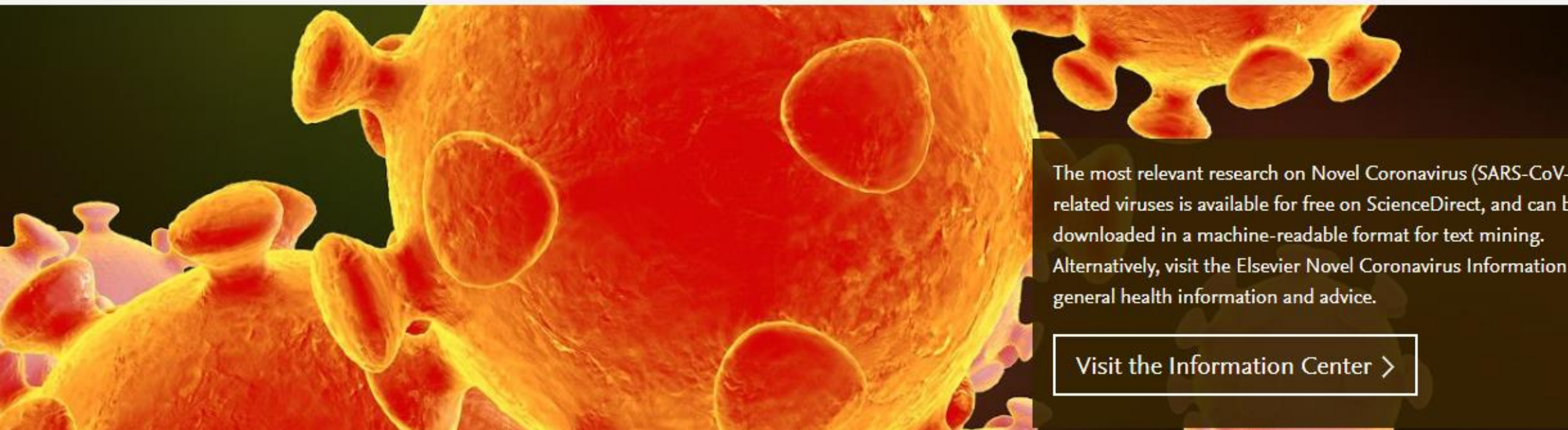
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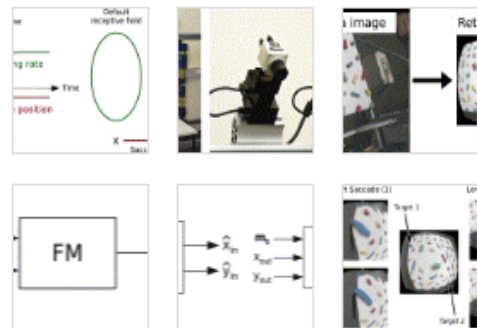
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New Ideas in Psychology

Volume 31, Issue 3, December 2013, Pages 221-238



Robot studies on visual prediction

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Abstract

Three robot studies on visual prediction are presented. In all of them, a visual

References

- Abrams et al., 1990 R.A. Abrams, S. Meyer, S. Kornblum
Eye hand coordination – control in rapid aimed limb movements
Journal of Experimental Psychology: Human Perception and Performance, 16 (1990), pp. 248-267
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- Afraz and Cavanagh, 2009 A. Afraz, P. Cavanagh
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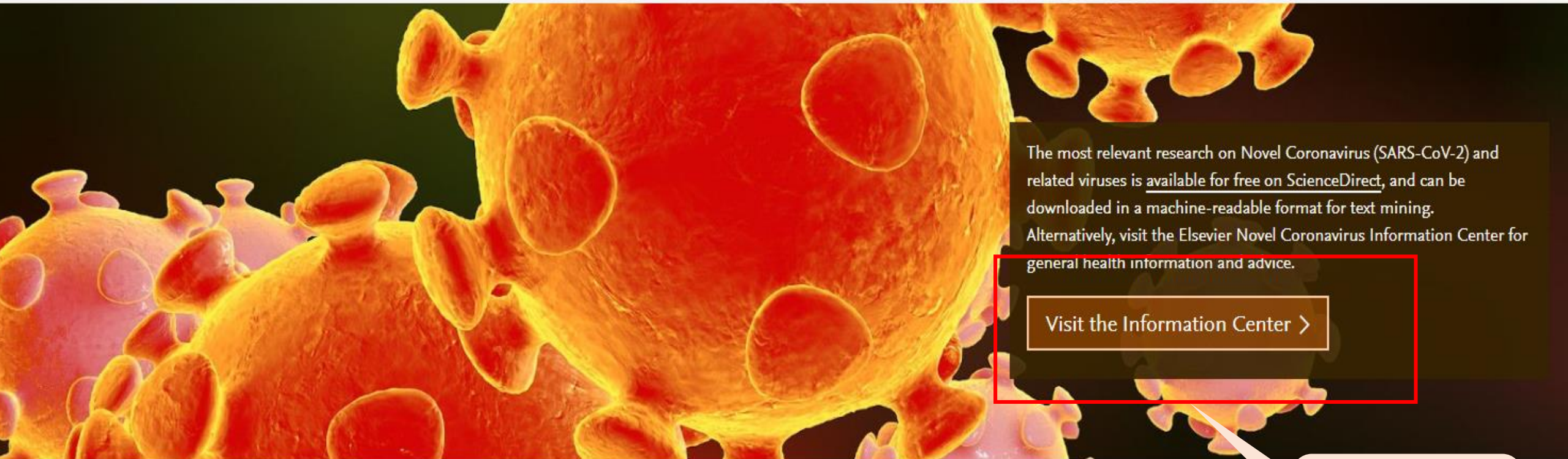
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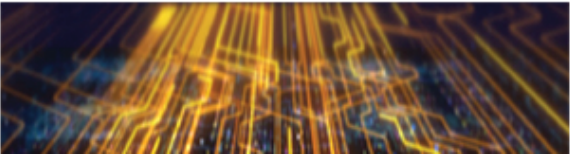
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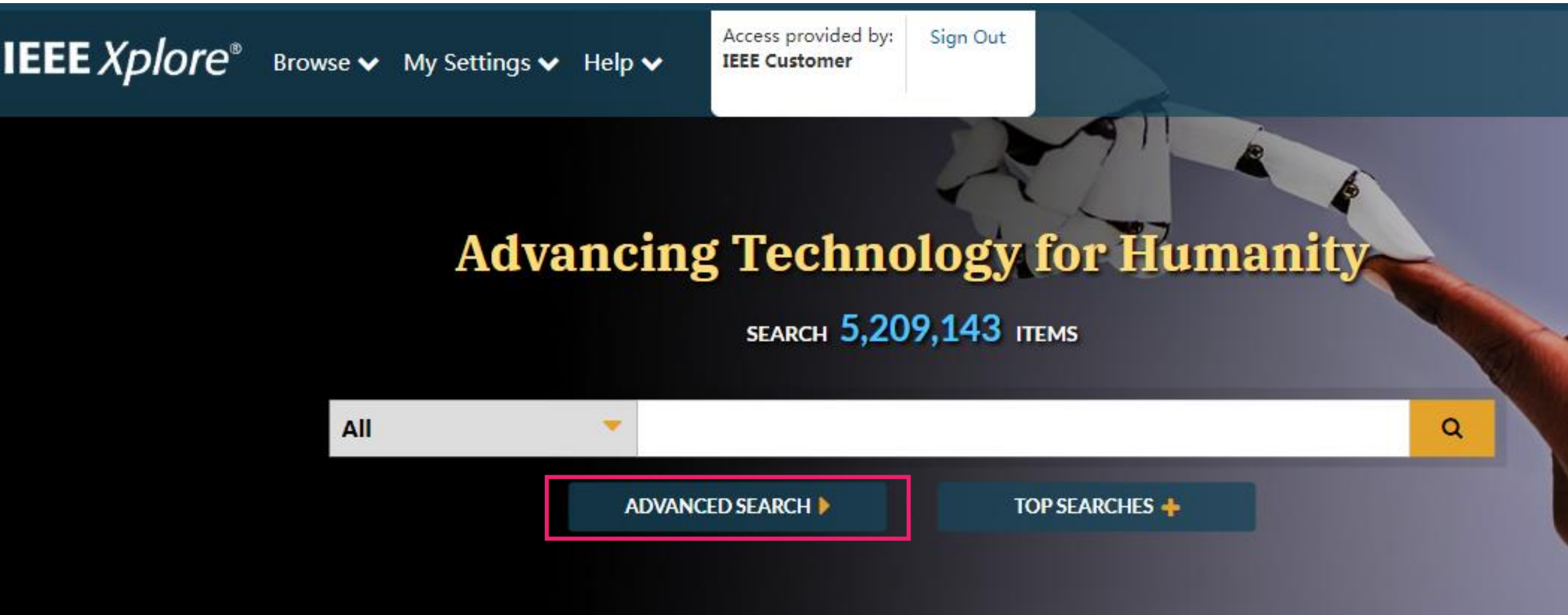
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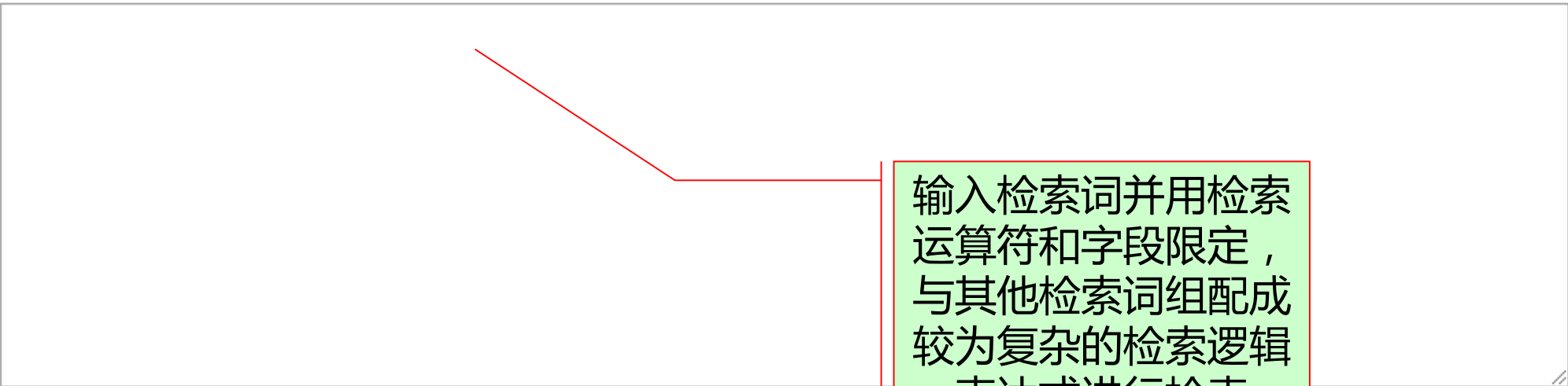


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From our observations in various kinds of museums, we discovered that guides routinely order to draw their attention towards both his/her explanation and sequences tend to begin with a pre-question which serves to not only monitor visitors' responses, but to also alert visitors that a primary question would be asked. We implemented this questioning-strategy with our robot system and investigated whether it was effective in human-robot interaction. We developed a vision system that enables the robot to monitor a visitor's response from the initial question. We evaluated the system in a real-world museum environment. The results showed that the robot's questioning strategy was effective in drawing visitors' attention towards the robot's explanation and in monitoring visitors' responses. The robot's questioning strategy was also effective in alerting visitors that a primary question would be asked. The robot's questioning strategy was also effective in monitoring visitors' responses. The robot's questioning strategy was also effective in alerting visitors that a primary question would be asked.

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From our observations in various kinds of museums, we discovered that guides routinely order to draw their attention towards both his/her explanation and sequences tend to begin with a pre-question which serves to not only monitor visitors' responses, but to also alert visitors that a primary question would be asked. We implemented this questioning-strategy with our robot system and investigated whether it was effective in human-robot interaction. We developed a vision system that enables the robot to monitor a visitor's response from the initial question. We evaluated the system in a real-world museum environment. The results showed that the robot's questioning strategy was effective in drawing visitors' attention towards the robot's explanation and in monitoring visitors' responses. The robot's questioning strategy was also effective in alerting visitors that a primary question would be asked.

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Implementing Human Questioning Strategies into Quizing-Robot

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ABSTRACT

From our ethnographic studies on various kinds of museums, we discovered that guides routinely propose questions to visitors in order to draw their attention towards both his/her explanation and the exhibit. The guides' question sequences tend to begin with a pre-question which serves to not only monitor visitors' behavior and responses, but to also alert visitors that a primary question would follow. We implemented this questioning-strategy with our robot system and investigated whether this strategy would also work in human-robot interaction. We developed a vision system that enables the robot to choose an appropriate visitor by monitoring a visitor's response from the initiation of a pre-question to the following pause. Results indicate that this questioning-strategy works effectively in human-robot interaction. In this experiment, the robot asked visitors about a photograph. At the pre-question, the robot delivered a rather easy question followed by a more challenging question (Figure 1). More participants turned their head away from the exhibition when they were not sure about their answer to the question. They either faced away from the robot, or smiled wryly at the robot or at each other. These types of behaviors index participants' states of knowledge, which we could utilize to develop a system by which the robot could choose an appropriate candidate by computational recognition.

ACM Classification Keywords

H5.2. Information interfaces and presentation (e.g., HCI): User Interfaces – interaction styles.

General Terms

Design, Experimentation, Human Factors.

Keywords

Interaction analysis, human-robot interaction, computer vision.



Figure 1. The robot asks an easy pre-question followed by a challenging question.

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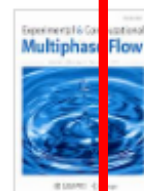
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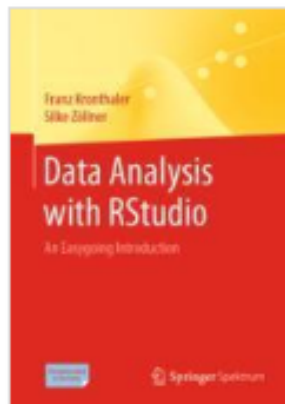
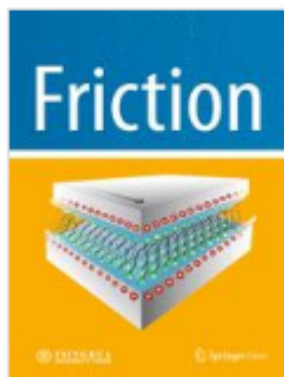
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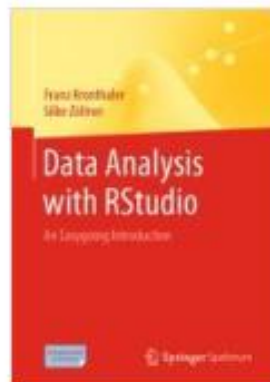
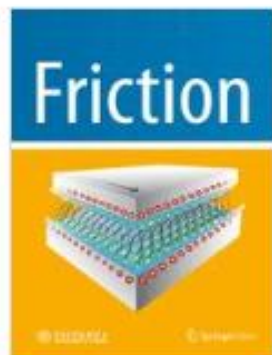
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Firefighting robots are actively being researched to reduce firefighter injuries and deaths as well as increase their effectiveness on performing tasks. There has been difficulty in making firefighting robots autonomous because the commonly used sensors for autonomous robot navigation do not perform well in fire smoke-filled environments where low visibility and high temperature are present. In order to overcome these limitations, a multi-spectral vision system was developed that uses sensor fusion between stereo thermal infrared (IR) vision and frequency modulated-continuous wave (FMCW) radar to locate objects through zero visibility smoke in real-time. In this system, the stereo IR vision was used to obtain 3-D information

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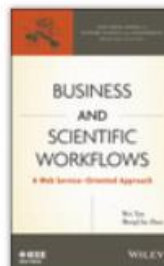


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The accuracy of the grinding robot's vision measurement system directly affects the machining accuracy. This study proposes a calibration method of the visual measurement system installed on the fourth joint of the ceramic billet grinding robot. This calibration method includes two steps: preliminary calibration and precise calibration. Preliminary calibration is to fit the transformation matrix between robot frame and vision measurement system frame by describing the same workpiece in different frames. In the precise calibration, the visual measurement error compensation model includes the kinematics error of the robot and the preliminary calibration error. The experimental results show that the calibration method proposed in this study can calibrate the three-dimensional (3D) vision measurement system of the robot with high precision. Besides, the repeated measurements of the same spatial point by the vision



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