

H – Personální zabezpečení – přednášející / Teaching Staff – Lecturer							
Název VŠ / součásti / Name of university / faculty	Université Paul Sabatier Toulouse, France						
Název SP / Name of study program	Electrical Engineering and Informatics / Engineering of Interactive Systems						
Jméno a příjmení / Lecturer (First name and last name)	Viviane Cadenat				Tituly / Titles	Dr.	
Rok narození / Year of birth	1972	typ vzt. / Type of employment	Full time	Rozsah / Range of employment	100%	Do kdy / employed till	
Přednášky v předmětech / Lectures in subjects	Robotics: manipulator and modelling mobile robots, visula servoing in robotics Automatics: analysis and control of continuous and digital systems						
Údaje o oboru vzdělání na VŠ a o praxi od absolvování VŠ, vč. studia v doktorském SP / Education, titles received and previous employment							
Education and earned degrees: 1996 M.Sc. in Automatics from National Schoul of Aeronautics and Space (ENSAE), Toulouse, France 1999 Ph.D. in Robotics from the Paul Sabatier University, Toulouse, France Career history: 1997-2000 Lecturer at Paul Sabatier University, Toulouse (as a part time employment), Since 2000 Associate Profesor at Paul Sabatier University, Toulouse							
Přehled o publikační a další tvůrčí činnosti za posledních 5 let / A short list of the most relevant publications and R&D achievements within in the last 5 years							
[1] D. Folio & V. Cadenat (2008), Dealing with visual features loss during a vision-based task for a mobile robot, International Journal of Optomechatronics, special issue on visual servoing, to appear in August 2008. [2] M. Courdresses & V. Cadenat (2007), A general approach for sensibility analysis in visual servoing, Advanced Robotics, Vol. 21, No 7, April 2007. [3] V. Cadenat, P.Souères & T. Hamel (2006), A reactive path-following controller to guarantee obstacle avoidance during the transient phase, International Journal of Robotics and Automation, Vol.21, N°4, 2006. [4] D. Folio & V. Cadenat (2007), A new controller to perform safe vision-based navigation tasks amidst possibly occluding obstacles, European Control Conference (ECC'07), Kos Island, Greece, July 2007. [5] D. Folio & V. Cadenat (2007), Using simple numerical schemes to compute visual features whenever unavailable. Application to a vision-based task in a cluttered environment, 4th International Conference on Informatics in Control, Automation and Robotics (ICINCO 2007), Angers, France, May 2007. [6] D. Folio & V. Cadenat (2006), A redundancy-based scheme to perform safe vision-based tasks amidst obstacles, IEEE International Conference on Robotics and Biomimetics (ROBIO'2006), Kunming, China, December 2006. [7] D. Folio & V. Cadenat (2005), A controller to avoid both occlusions and obstacles during a vision-based navigation task in a cluttered environment, European Control Conference and Conference on Decision and Control (ECC/CDC'05), Sevilla, Spain, December 2005. [8] D. Folio & V. Cadenat (2005), Using redundancy to avoid simultaneously occlusions and collisions while performing a vision-based task amidst obstacles, 2 nd European Conference on Mobile Robots, Ancona, Italy, September 2005. [9] P. Souères, V. Cadenat & M. Djeddou (2003), Dynamical sequence of multi-sensor based tasks for mobile robots navigation, 7th Symposium on Robot Control (SYROCO'03), Wroclaw, Poland, September 2003.							
Působení v zahraničí / Stays abroad							
Obor habilitačního nebo jmenovacího řízení nebo udělení vědecké hodnosti / Habilitation and PhD degree – Branch			Multi-sensor based control strategies for manipulator arms and mobile robots			ohlasy publikací / number of SCI citations	
Habilitation and PhD degree - year and institution		PhD degree from Paul Sabatier University (Toulouse), December 1999.			Mezinár. / international		tuzem. / national
Podpis přednášejícího / Lecturer signature					Datum / date		26 May 2008