TECHNICAL PROGRAM

July 3, 2006, Monday

8:00 – 17:00 REGISTRATION

9:00 – 9:15 OPENING CEREMONY Room Mátyás I-II
Chair: Imre J. Rudas
Budapest Tech, Hungary

9:15 – 10:00 PLENARY SESSION I Room Mátyás I-II
Chair: Imre J. Rudas
Budapest Tech, Hungary

Multimodal Sensing and Computing with Thousands of Processors
Tamás Roska
Hungarian Academy of Sciences

10:00 – 10:20 COFFEE BREAK

10:20 – 12:20 PARALLEL SESSION Room Mátyás I-II

Motion Control and Position Control

Chair: Antal Huba
Budapest University of Technology and Economics, Hungary

10:20 Omnidirectional Image Matching for Vision-Based Robot Localization
Mana Saedan, Marcelo H. Ang Jr., Chee Wang Lim
Singapore

10:40 Design and Manufacturing of Ultra Small Actuator
Joo Han Kim, In Sung Chung, Ha Kyeong Sung
Korea

11:00 2DOF Control-Based Fast and Precise Positioning for Vibratory Mechanism with Nonlinear Friction
Makoto Iwasaki, Motohiro Kawafuku, Hiromu Hirai
Japan

11:20 Research on Fault Diagnosis of Gearbox Based on Particle Swarm Optimization Algorithm
Pan Hongxia, Ma Qingfeng, Wei Xiuye
China
11:40 Design and Application of a Motion Platform for a High-Speed Craft Simulator
Webjorn Rekdalsbakken
Norway

12:00 The Wafer Alignment Algorithm Regardless of Rotational Center
HyungTae Kim, HaeJeong Yang, SungChul Kim
South Korea

10:20 – 12:20 PARALLEL SESSION Room Krisztina

Control Theory

Chair: Stefan Preitl
“Politehnica” University of Timisora, Romania

10:20 Approaches of Discrete Feedforward Control for Vibration Cancellation in Multimode Single-Link Flexible Manipulators
Emiliano Pereira, Iván M. Díaz, Pedro Roncero, Vicente Feliu
Spain

10:40 Model Based Quality Assurance and Self-management within a Software Architecture for Parallel Kinematic Machines
Jens Steiner, Michaela Huhn, Tilo Mücke
Germany

11:00 Information Gap between Technology Specialists and Decision Makers
Josef Hynek, Václav Janecek
Czech Republic

11:20 A Modified DNA-Computing Algorithm to Solve TSP
Kourosh Mehdizadeh, M. A. Nekoui, Kamel Sabahi, Adel Akbarimajd
Iran

11:40 Project Course 'Design of Mechatronic Systems'
Christian Koch, Oliver Radler, Alexander Spröwitz, Tom Ströhla, Veit Zöppig
Germany

12:00 Disturbance Rejection of Left Invertible Neutral Time Delay Systems
Paraskevas N. Paraskevopoulos, Fotis N. Koumboulis, George E. Panagiotakis
Greece

12:20 – 14:00 LUNCH TIME
14:00 – 16:00 PARALLEL SESSION Room Mátyás I-II

Driving System

Chair:  
László Horváth  
Budapest Tech, Hungary

14:00  
Magnetic Flux Distribution in the Air-Gap of Cylindrical- and Disc-Form DC Micromotors used for Mobile Phones  
Attila Lukács, Attila Halmai  
Hungary

14:20  
Modelling of the Linear Ultrasonic Motor using an Elliptical Shape Stator  
Shine-Tzong Ho  
Taiwan

14:40  
On the Usefulness of Simulation in Designing a Permanent Magnet Modular surface Motor for Advanced Mechatronic Systems  
Loránd Szabó, Dan-Cristian Popa, Vasile Iancu, Ernő Kovács, Ferenc Tóth  
Romania, Hungary

15:00  
Direct Drive Rotary Servomotor for Semiconductor Applications  
Liu Yuan-Jiang, Zhu Qixin, S. Y. Ho, G. P. Widdowson  
Hong Kong

15:20  
Real-Time Emulator of Magnetic Suspension System for FPGA-based Controller  
Rafal Jastrzebski, Riku Pöllänen, Olli Pyrhönen  
Finland

15:40  
System Configuration of Tri-pole Magnetic Bearings  
Ping-Ho Chen  
Taiwan

13:40 – 16:00 SPECIAL SESSION Room Krisztina

Vehicle Dynamics

Chairs:  
Bodo Heimann and Dieter Schramm  
University of Hannover, Germany  
University of Duisburg-Essen, Germany

13:40  
Enhancement of the Stability Control System with Steering Intervention in Commercial Vehicles  
László Palkovics  
Hungary
14:00 Diagnosis of Active Dynamic Control Systems Using Virtual Sensors and Observers
    Keiwan Kashi, Dirk Nissing, Dirk Kesselgruber, Dirk Söffker
    Germany

14:20 Modeling and Simulation of the Effect of Reversible Belt Pretensioners
    Cem Kurutas, Dieter Schramm, Konrad Elsäßer, Manfred Hiller
    Germany

14:40 A Simulation Environment for Field Relevant Rollover Accidents
    Karina Hirsch, Dieter Schramm
    Germany

15:00 Modelling and Identification of Car Driveline Dynamics for Anti-jerk Controller Design
    Martin Grotjahn, Lars Quernheim, Steffen Zemke
    Germany

15:20 Road-Wheel Interaction in Vehicles - A Mechatronic View of Friction
    Bodo Heimann, Noamen Bouzid, Ahmed Trabelsi
    Germany

15:40 On-Board Payload Identification for Commercial Vehicles
    Werner Kober, Wolfgang Hirschberg
    Austria

16:00 – 16:20 COFFEE BREAK

16:20 – 18:00 PARALLEL SESSION Room Mátyás I-II

Machine Vision
Chair: Josef Hynek
     Czech Republic

16:20 Non-homogenous Illumination Correction of Calibrated Incoherent Optical-fiber-bundles for Image Transmission Purposes
    Olivier Demuynck, José Luis Lázaro, Oscar Esteban, Daniel Pizarro
    Spain

16:40 Computer Aided Color-encoded Moiré Contouring
    Daria Paveleva, Ákos Antal
    Hungary
17:00  Using Conical and Spherical Mirrors with Conventional Cameras for 360° Panorama Views in a Single Image
João Carlos Aparício Fernandes, José Alberto B. Campos Neves
Portugal

17:20  Design Considerations for a Modular High Precision 3D Coordinate Measuring Machine
Gyula Hermann
Hungary

17:40  Summarization Analysis and Development Tendency of General Profiles for Scroll Compressor
Licun Wang, Jin Chen
China

16:20 – 18:00 PARALLEL SESSION  Room Krisztina

Noise and Vibration
Chair: Ismael Payo
University of Castilla-La Mancha, Spain

16:20  A Virtual Microphone Feedback Control System for Active Noise Control
Wen-Kung Tseng, Ying-Pin Chang
Taiwan

16:40  Frequency Variation for the Purpose of Vibration Isolation
Ahmed Abu Hanieh, André Preumont
Palestine, Belgium

17:00  Measurement and Analysis of Noise Characteristics for Diesel Engine
Liu Guangpu, Pan Hongxia
China

17:20  Image Smoothing and Edge Detection CMOS Sensor Array with Improved Signal Output Range
Tamás Zeffer, Jerry Yeargan
Hungary, USA

17:40  A Research on Reconfigurable Numerical Controller Based on Embedded System
Wenbin Wang, Tao Yu, Tan Liu
China

18:30 – WELCOME RECEPTION  Hotel Buda
8:00 – 17:00 REGISTRATION

9:00 – 9:45 PLENARY SESSION II Room Mátyás I-II

Chair: Karel Jezernik
Maribor, Slovenia

Computational Intelligence for Nonlinear Systems
Bogdan M. Wilamowski
Auburn University, USA

9:45 – 10:05 COFFEE BREAK

10:05 – 12:05 PARALLEL SESSION Room Mátyás I-II

Fuzzy Control

Chair: Mártá Takács
Budapest Tech, Hungary

10:05 A Layered Fuzzy Controller for Nonholonomic Car-Like Robot Motion Planning
Mohamed M. El-Khatib, David J. Hamilton
United Kingdom

10:25 Fault Diagnosis for an Aircraft Engine Based on Information Fusion
Li Changzheng, Lei Yong
China

10:45 Fuzzy Control Solution for a Class of Tricycle Mobile Robots
Radu-Emil Precup, Stefan Preitl, Zsuzsa Preitl
Romania, Hungary

11:05 Design and Implementation of Biaxial Motion Control Systems Using Fuzzy Logic Based Adjustable Feedrate
Ke-Han Su, Chi-Yun Hsieh, Ming-Yang Cheng
Taiwan

11:25 Optimising the Distance-gap between Cars by Fuzzy-Interpolative Control with Time to Collision Planning
Marius Mircea Balas, Valentina E. Balas
Romania

11:45 Optimisation of Fault-Tolerant Fabric-Cutting Table Planning in a Just-In-Time Apparel Manufacturing Environment
Pin Yin Mok, Wai-Keung Wong, Chun-Kit Kowng
Hong Kong
10:05 – 12:05 PARALLEL SESSION  Room Krisztina

Man-Machine System

Chair: Fetah Kolonic
University of Zagreb, Croatia

10:05 Easy Human Interface for Severely Handicapped Persons and Application for Eating Assist Robot
Yoshihiko Takahashi, Shinichiro Suzukawa
Japan

10:25 Human-Oriented Design of Autonomous Navigation Assisted Robotic Wheelchair for Indoor Environments
Chung-Hsien Kuo, Hayato H. W. Chen
Taiwan

10:45 High Elastic Bionic Based Robot and Gripper
József Keskeny, Antal Huba, István Muka
Hungary

11:05 Rapid Prototyping of Mechatronic Systems with Mixed Continuous and Discrete-Event Dynamics
Karel Jezernik, Ales Polic, Ales Hace
Slovenia

11:25 Virtual Space for Intelligent Engineering in Mechatronics
László Horváth, Imre J. Rudas
Hungary

11:45 Embedded Control System Architecture applied to an Unmanned Aerial Vehicle
Jaime del-Cerro, Antonio Barrientos, Jorge Artieda, Enrique Lillo, Pedro Gutierrez, Rodrigo San Martín
Spain

10:05 – 12:05 SPECIAL SESSION  Room Szent István

The Role of Multi-agent Systems in the Solution of Intelligent Manufacturing Systems

Chair: Baltazár Frankovic
Slovak Academy of Sciences

10:05 Adopting RFID in Supply Chains
Péter Németh, Lajos Tóth, Tamás Hartványi
Hungary

10:25 Central Ontology Layer for Power Grid Scheduling
Ivana Budinská, Viktor Oravec, Baltazár Frankovic
Slovakia
10:45 Who Moved?! An Investigation into Distribution of Actions and Behaviors in a Multi Agent System  
Roozbeh Daneshvar, Caro Lucas  
Iran

11:05 Multiagent Hybrid Control of Electric-Energy Systems  
Ján Sarnovsky, Martin Dula, Peter Kica  
Slovakia

11:25 Agent-based Solutions to Support Car Recycling  
George L. Kovács, Géza Haidegger  
Hungary

11:45 Coalition Logic of Propositional Control Based Multi Agent System Modeling  
Viktor Oravec, Jaroslav Fogel  
Slovakia

12:05 – 13:30 LUNCH TIME

13:30 – 15:30 PARALLEL SESSION  
Room Mátyás I-II

Fuzzy Control and Neural Network

Chair: Mahrdad Moallem  
University of Western Ontario, Canada

13:30 Grey Prediction Based Control of a Non-Linear Liquid Level System Using PID Type Fuzzy Controller  
Erdal Kayacan, Okyay Kaynak  
Turkey

13:50 Modified Distance-based Operators in Fuzzy Approximate Reasoning  
Márta Takács  
Hungary

14:10 The Robust Harmonic Filter Design Using Artificial Neural Network and Taguchi Method  
Ying-Pin Chang, Wen-Kung Tseng  
Taiwan

14:30 Implementation of Control Algorithms in a System-on-a-Programmable-Chip  
Maciej Petko, Grzegorz Karpiec  
Poland

14:50 The Configurable Digital Neural Network with Emulated Digital Cellular Neural Network Cores  
Tamás Zeffer, Timót Hidvégi  
Hungary
15:10  Precision Position Control of PMSM Using Neural Network Disturbance Observer on Forced Nominal Plant  
*Jong-Sun Ko, Byung-Moon Han*  
South Korea

13:30 – 15:30 SPECIAL SESSION  
Room Krisztina

**Introduction and First Results of a Joint Hungarian-German Research Base (Huge-Rb) on Mechatronics**

**Chairs:**  
*Dieter Schramm and Gyula Patkó*  
University of Duisburg-Essen, Germany  
University of Miskolc, Hungary

13:30  **Online Quality Prediction in Injection Molding Processes**  
*Johannes Wortberg, Reinhard Schiffers*  
Germany

13:50  **Development of Mechatronic System at the Institute for Mechatronics at the University of Miskolc**  
*Attila Szilágyi, Gyula Patkó, György Hegedus, Tibor Csáki, György Takács*  
Hungary

14:10  **Hungarian-German Joint Research Base (HUGE-RB) on Mechatronics**  
*Dieter Schramm, Michael Unterreiner, Gyula Patkó*  
Germany

14:30  **The Robert Bosch Chair for Mechatronics in Miskolc, Advanced Concepts for Lectures and Research**  
*Endre Jakab, Gyula Patkó, Attila Szilágyi*  
Hungary

14:50  **Feature-Based Fault Detection Approaches**  
*Markus Özbek, Dirk Söffker*  
Germany

15:10  **The Newest Research Results at Automatized Mechatronics Logistics**  
*József Cselényi, Béla Illés, Levente Rádai*  
Hungary
13:30 – 14:30 SPECIAL SESSION Room Szent István
Sensorics and Control of Mobile Vehicles

Chair: László Vajta
Budapest University of Technology and Economics, Hungary

13:30 Projective Reconstruction for Robot Vision System
Ferenc Tél, Béla Lantos
Hungary

13:50 Extension of the Rapidly Exploring Random Tree Algorithm with Key Configurations for Nonholonomic Motion Planning
Emese Szádeczky-Kardoss, Bálint Kiss
Hungary

14:10 Modeling, Identification, and Control of Harmonic Drives for Mobile Vehicles
László Lemmer, Bálint Kiss
Hungary

14:30 – 15:30 SPECIAL SESSION Room Szent István
Mechatronic Design Methodology at Third Level Education

Chair: Mohamad Saleh
Ireland

14:30 A Bottom Up Approach to Teaching Mechatronics
Zvi Shiller, Sigal Berman
Israel

14:50 Mechatronics at Third Level Education: Practical Design Considerations
Mohamad Saleh
Ireland

15:10 Programmable Logic Controller Programming - A Proposed Protocol for Procurement and Development, with Special Relevance to Training and Education
James Prendergast, Michael Barrett
Ireland

15:30 – 15:50 COFFEE BREAK
15:50 – 17:30 PARALLEL SESSION Room Mátyás I-II

Telemanipulation
Chair: István Loványi
Budapest University of Budapest and Technology, Hungary
15:50 A Study of Transparency in Wave-Based Teleoperation
Arash Aziminejad Mehrdad Moallem Rajni V. Patel
Canada
16:10 Iterative Learning Control of a Direct Driven Spatial Parallel Manipulator
Houssem Abdellatif, Bodo Heimann
Germany
16:30 Some Problems and Problematic Solutions of Secure Hot-plug
Elemér Károly Nagy, István Loványi
Hungary
16:50 A Granular-based Method for Position and Reliability Estimation in Alarm Systems
Barna Cornel
Romania
17:10 Exponential Stability Synthesis of Networked Nonlinear Control Systems in FMS
Dan Ma, Jovan D. Stefanovski, Georgi M. Dimirovski, Jun Zhao
China, Macedonia, Turkey

15:50 – 17:30 PARALLEL SESSION Room Krisztina

Mobile Robotics I
Chair: Jens Steiner
Technical University of Braunschweig, Germany
15:50 Power Analysis for a Skid-Steered Tracked Mobile Robot
Jesús Morales, Jorge L. Martínez, Anthony Mandow, Alfonso J. García-Cerezo, Jesús M. Gómez-Gabriel and Salvador Pedraza
Spain
16:10 Position and Orientation Control of a Mobile Wheeled Pendulum Moving on an Inclined Plane
Danielle Sami Nasrallah, Jorge Angeles, Hannah Michalska
Canada
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<th>Time</th>
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| 16:30  | Feasibility Study of the Form and Structure of a Ball-like Mobile Robot for Indoor Environments  
*Marek Matusiak, Pekka Appelqvist, Janne Paanajärvi, Tomi Ylikorpi, Aarne Halme*  
Finland  
| 16:50  | Automatically Controlled Vibration-driven Robots  
*Nikolai N. Bolotnik, Sergey F. Jatsun, Andrey S. Jatsun, Andrey A. Cherepanov*  
Russia  
| 17:10  | A Comparison of Bayesian Prediction Techniques for Mobile Robot Trajectory Tracking  
*José-Luis Peralta-Cabezas, Marcelo Guarini-Herrmann, Miguel Torres-Torriti*  
Chile  
| 15:50 – 17:30 SPECIAL SESSION  
Room Szent István  
Automation Through Mechatronics Applications in Rural Industry  
*Chair:*  
*Yousef Ibrahim*  
Monash University, Australia  
| 15:50  | Slip Angles and Longitudinal Slip Measurement of the Cooperative Redundant Steering/Drive System  
*I. J. Spark, M. Yousef Ibrahim*  
Australia  
| 16:10  | Decision Support Systems in Agribusiness  
*Fotis N. Koumboulis, Maria P. Tzamtzi, Martin Pavlovic*  
Greece, Slovenia  
| 16:30  | Study on Fresh Fish Sorting Techniques  
*M. Yousef Ibrahim, S. Sultana*  
Australia  
| 16:50  | Adaptive Multi-scale Vision System for Robotic Applications  
*András Barta, István Vajk*  
Hungary  
| 17:10  | Machine Vision in an Automated Component-Handling System  
*Gert D. Jordaan, Ruhan Jansen van Nieuwenhuizen*  
South Africa  
| 18:30  | Bus leaves from Hotel Buda for riverside  
| 19:00 – 22:00 | Banquet – Cruising on river Danube  
*bus transfer is provided back to the hotel* |
July 5, 2006, Wednesday

8:00 – 15:00 REGISTRATION

9:00 – 10:40 PARALLEL SESSION Room Mátyás I-II

Mobile Robotics II
Chair: George Chamilothoris
Piraeus Institute of Technology, Greece

9:00 A New Architecture to Execute CAs-Based Path-Planning Algorithm in Mobile Robots
Adel Akbarimajd, Caro Lucas
Iran

9:20 Control of a Fleet of Vehicles Using Computer Vision, Cellular Automaton and Genetic Trained Behaviour
Nera González Romero, Jorge Artieda Trigueros
Spain

9:40 Robust Asymptotic Output Tracking for Four-Wheel-Steering Vehicles
Michael G. Skarpetis, Fotios N. Koumboulis, Achileas S. Ntollis, George Chamilothoris
Greece

10:00 Design and Realization of a Biped Robot Using Stepper Motor Driven Joints
Ákos Tar, József Veres, György Cseréy
Hungary

10:20 Decoupling Control Algorithms for 4WS Vehicles
Michael G. Skarpetis, Fotios N. Koumboulis, Fokionas S. Barmpokas, George E. Chamilothoris
Greece

9:00 – 10:40 SPECIAL SESSION Room Krisztina

Sophisticated Methods in Motion Planning and Control
Chairs: József K. Tar and Krzysztof Kozlowski
Budapest Tech, Hungary
Poznan University of Technology, Poland

9:00 Stable Adaptive Ball and Beam Control
Lőrinc Mártson, Béla Lantos
Romania, Hungary
9:20 Stabilization of the Adaptive Control of a 4th Order System Using Coordinate and Velocity Potentials
Imre J. Rudas, József K. Tar, Kazuhiro Kosuge
Hungary, Japan

9:40 Practical Stabilization of a Skid-steering Mobile Robot - A Kinematic-based Approach
Krzysztof Kozłowski, Dariusz Pazderski
Poland

10:00 Motion Planning Methods for Stratified Systems
István Harmati
Hungary

10:20 Eigenvalue Properties of Discrete Time Linear Receding Horizon Control Systems
Ádám Varga, Béla Lantos
Hungary

9:00 – 10:40 SPECIAL SESSION Room Szent István
Intelligence Space & Cognitive Models
Chairs: Hideki Hashimoto and Péter Korondi
University of Tokyo, Japan
Budapest University of Technology and Economics, Hungary

9:00 Visual Feature Array based Cognitive polygon recognition using the UFEX text categorizer
Barna Reskó, Domonkos Tikk, Hideki Hashimoto, Péter Baranyi
Hungary, Japan

9:20 Human Walking Behavior Model for Intelligent Space
Péter T. Szemes, Péter Korondi, Hideki Hashimoto
Hungary, Japan

9:40 Visual Cortex Inspired Vertex and Corner Detection
Ádám Csapó, András Róka, Péter Baranyi
Hungary

10:00 Virtual Master Device for Telemanipulation
Béla Takarics, Péter T. Szemes, Péter Korondi
Hungary

10:40 – 11:00 COFFEE BREAK
11:00 – 13:00 PARALLEL SESSION  Room Mátyás I-II

Robot Control I

Chair:  Béla Lantos
Budapest University of Technology and Economics, Hungary

11:00 Development of a Network-based Real-Time Robot Control System over IEEE 1394: Using Open Source Software Platform
M. Omar Faruque Sarker, ChangHwan Kim, Jeong-San Cho, Bum-Jae You
Korea

11:20 Force-Torque Control for an Experimental Robot Controller
István Oláh, Gábor Tevesz
Hungary

11:40 Force Control of a Single-Link Flexible Arm
Ismael Payo, Vicente Feliu, Mehrdad Moallem
Spain, Canada

12:00 Quaternion Based Inverse Kinematics for Industrial Robot Manipulators with Euler Wrist
Yavuz Aydin, Serdar Kucuk
Turkey

12:20 An Environment for Programming and Control of Multi-Robot Manipulators
Mahrdad Moallem, R. Khoshbin
Canada

12:40 Design of a Robot for Transperineal Prostate Needle Placement in MRI Scanner
Gregory S. Fischer, Iulian Iordachita, Simon P. DiMaio, Gabor Fichtinger
USA

11:00 – 12:40 SPECIAL SESSION  Room Krisztina

Advanced Motion Control

Chairs:  Kouhei Ohnishi and Seiichiro Katsura
Keio University, Japan
Nagaoka University of Technology, Japan

11:00 Time Delay Compensation in Bilateral Teleoperation Systems
Kenji Natori, Kouhei Ohnishi
Japan
11:20  Skill Acquisition of Human Fingers Based on Interaction Mode Control
Seiichiro Katsura, Toshiyuki Suzuyama, Kiyoshi Ohishi
Japan

11:40  Reproduction of Real World Force Sensation by Bilateral Motion Control Based on Contact Impedance Model Taking Environmental Hysteresis into Account
Tomoyuki Shimono, Seiichiro Katsura, Kouhei Ohnishi
Japan

12:00  Cooperative Mobile Manipulator with Dual Compliance Controllers based on Estimated Torque and Visual Force
Abdul Muis, Kouhei Ohnishi
Japan

12:20  The Tinyphoon’s Control Concept
Gregor Novak, Charlotte Roesener, Markus Bader, Tobias Deutsch, Stefan Jakubek, Stefan Krywult, Martin Seyr
Austria, Japan

12:40 – 14:00  LUNCH TIME

14:00 – 15:20  PARALLEL SESSION  Room Mátyás I-II

Robot Control II
Chair: Rafal Jastrzebski
Lappeenranta University of Technology, Finland

14:00  Robust Gamma-Stable Controller Design for a Two-Degree-of-Freedom Robot Arm
László Lemmer, Bálint Kiss
Hungary

14:20  Trajectory Control of Robot with Model Reference Zero Vibration Shaper
Timothy Chang, Ding Yuan
United States

14:40  Design and Control of Three-Robot Visual Servoing Mechatronics System
Mahdi Ahmadi, Mohammad Eghtesad, Dan S. Necsulescu
Iran

15:00  Control of Robot Endpoint on Surface
Václav Záda
Czech Republic
TP Model Transformation-based Control

Chairs: Péter Baranyi and Péter Korondi
Budapest University of Technology and Economics, Hungary

14:00 Decrease of the Computational Load of TP Model Transformation
Zoltán Petres, Péter Baranyi, Hideki Hashimoto
Hungary, Japan

14:20 Definition of the HOSVD-based Canonical Form of Polytopic Dynamic Models
Péter Baranyi, László Szeidl, Péter Várlaki, Yeung Yam
Hungary, Hong Kong

14:40 Experimental Control Design by TP Model Transformation
Fetah Kolonic, Alen Poljugan
Croatia

15:00 Sliding Surface Design Based on TP Model Transformation
Péter Korondi
Hungary

15:30 – CLOSING CEREMONY

Chair: Imre J. Rudas