

Semantic Web Technologies for Improving Remote Visits of Museums, using a Mobile Robot

Michel Buffa, Catherine Faron Zucker, Thierry Bergeron, Hatim Aouzal
WIMMICS research team
Université Côte d'Azur, CNRS, INRIA, I3S, France



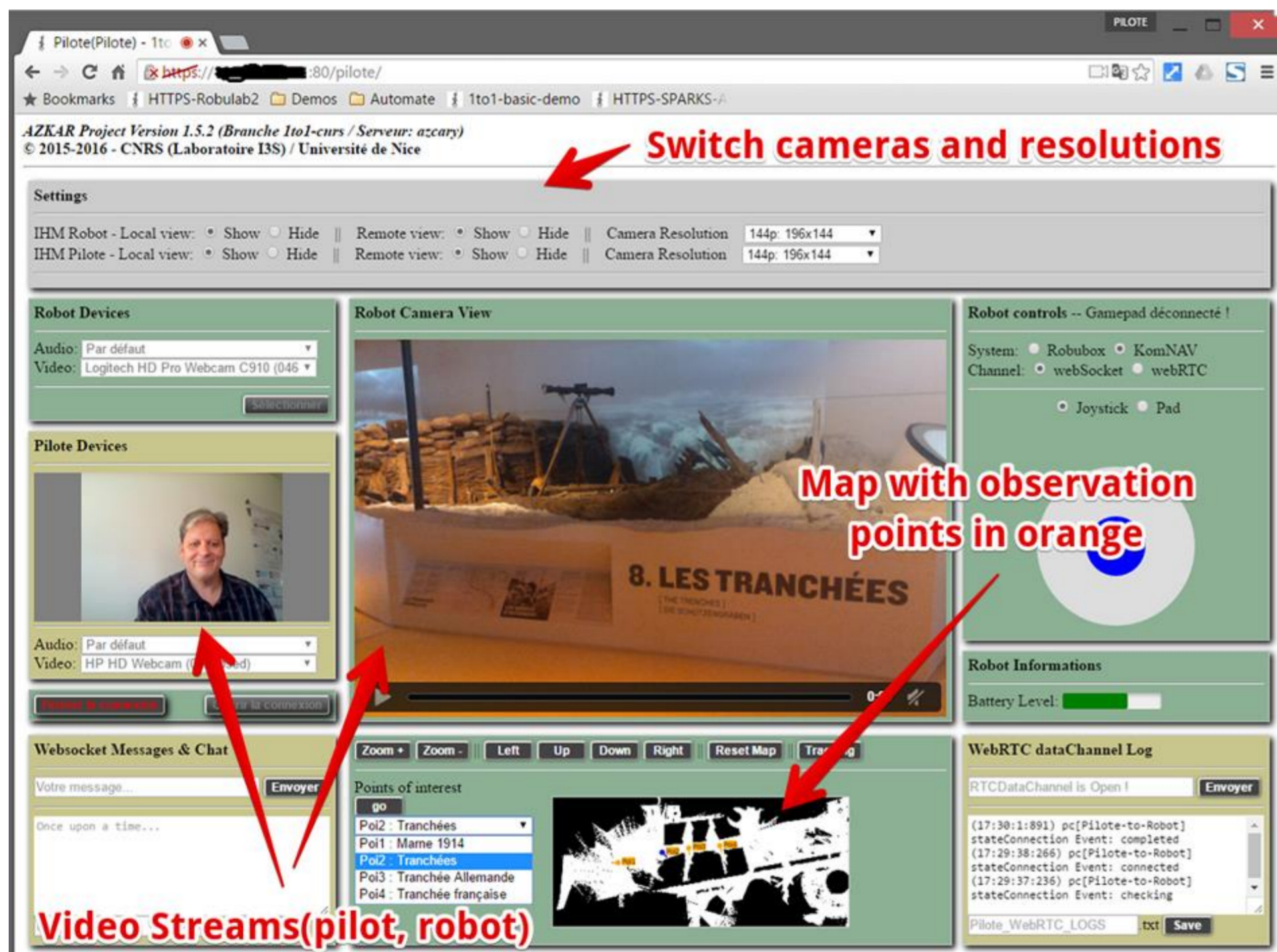
Mobile robot in the World War 1 Museum

Mobile robot remotely controlled using a P2P connection via WebRTC

When entering the museum, the robot downloads in its triplestore the museum's RDF dataset & the AMO ontology that describes scenes, objects, paths and linked multimedia documents.

SPARQL queries are triggered by sensors and geolocation when the robot returns the name of the POI where it is located. They return the scene descriptions and links to medias related to the POI.

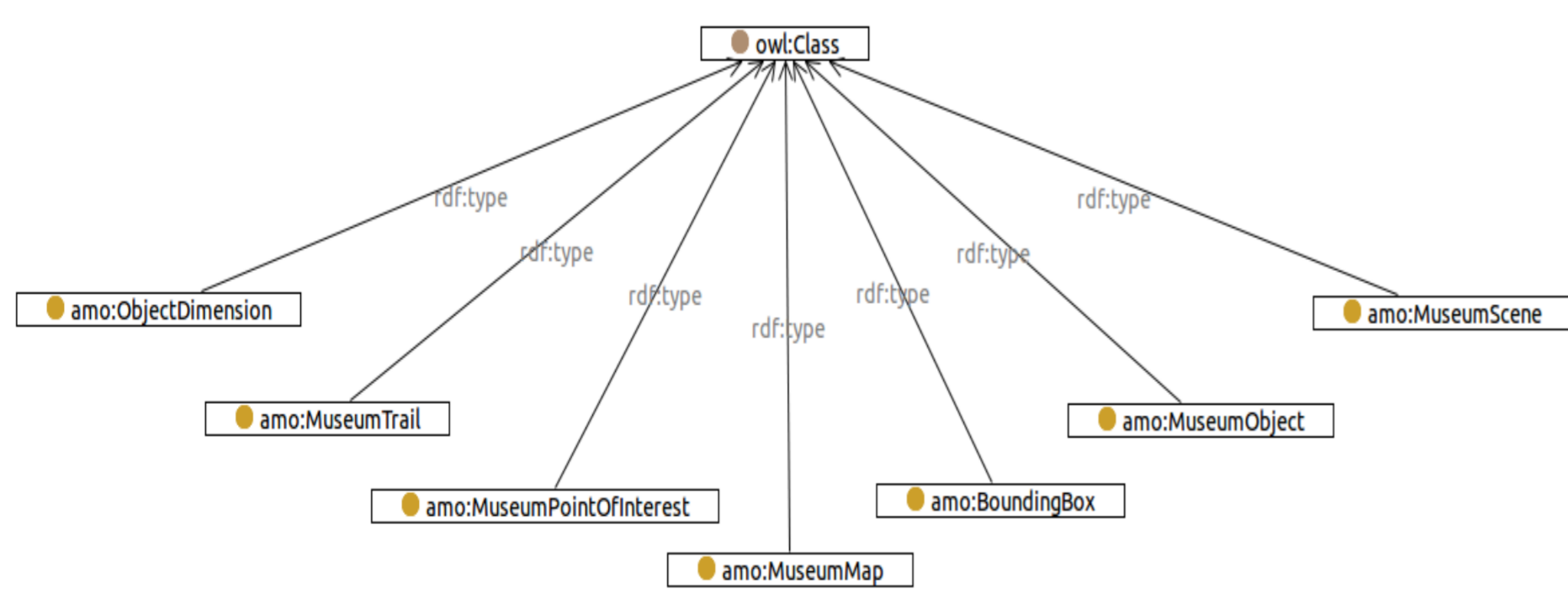
Trails between POIs are calculated autonomously by the robot.



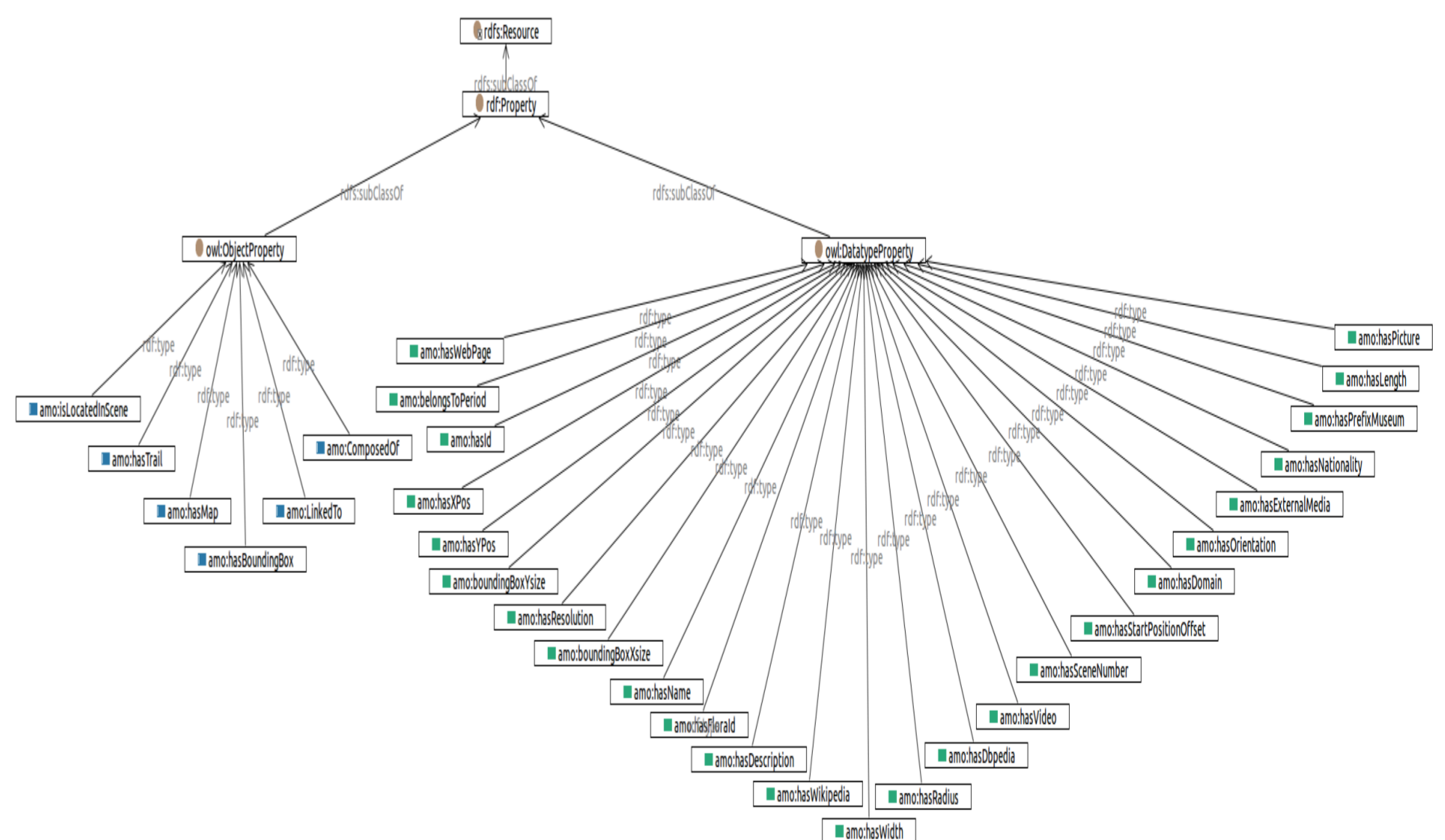
Remote client in standard mode



Remote client in fullscreen mode



AMO ontology classes



AMO ontology property subset