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Bruno Siciliano, Oussama Khatib

Build Your Own Paper Robots Julius Perdana,Josh Buczynski,Kurt Young,2009-08-18 Presents projects, instructions, and color templates for fourteen paper robots.

Arduino Robotics John-David Warren,Josh Adams,Harald Molle,2011-10-08 This book will show you how to use your Arduino to control a variety of different robots, while providing step-by-step instructions on the entire robot building process. You'll learn Arduino basics as well as the characteristics of different types of motors used in robotics. You also discover controller methods and failsafe methods, and learn how to apply them to your project. The book starts with basic robots and moves into more complex projects, including a GPS-enabled robot, a robotic lawn mower, a fighting bot, and even a DIY Segway-clone. Introduction to the Arduino and other components needed for robotics Learn how to build motor controllers Build bots from simple line-following and bump-sensor bots to more complex robots that can mow your lawn, do battle, or even take you for a ride Please note: the print version of this title is black & white; the eBook is full color.

Introduction to Autonomous Mobile Robots, second edition Roland Siegwart,Illah Reza Nourbakhsh,Davide Scaramuzza,2011-02-18 The second edition of a comprehensive introduction to all aspects of mobile robotics, from algorithms to mechanisms. Mobile robots range from the Mars Pathfinder mission's teleoperated Sojourner to the cleaning robots in the Paris Metro. This text offers students and other interested readers an introduction to the fundamentals of mobile robotics, spanning the mechanical, motor, sensory, perceptual, and cognitive layers the field comprises. The text focuses on mobility itself, offering an overview of the mechanisms that allow a mobile robot to move through a real world environment to perform its tasks, including locomotion, sensing, localization, and motion planning. It synthesizes material from such fields as kinematics, control theory, signal analysis, computer vision, information theory, artificial intelligence, and probability theory. The book presents the techniques and technology that enable mobility in a series of interacting modules. Each chapter treats a different aspect of mobility, as the book moves from low-level to high-level details. It covers all aspects of mobile robotics, including software and hardware design considerations, related technologies, and algorithmic techniques. This second edition has been revised and updated throughout, with 130 pages of new material on such topics as locomotion, perception, localization, and planning and navigation. Problem sets have been added at the end of each chapter. Bringing together all aspects of mobile robotics into one volume, Introduction to Autonomous Mobile Robots can serve as a textbook or a working tool for beginning practitioners. Curriculum developed by Dr. Robert King, Colorado School of Mines, and Dr. James Conrad, University of North Carolina-Charlotte, to accompany the National Instruments LabVIEW Robotics Starter Kit, are available. Included are 13 (6 by Dr. King and 7 by Dr. Conrad) laboratory exercises for using the LabVIEW Robotics Starter Kit to teach mobile robotics concepts.

Proceedings of ICRIC 2019 Pradeep Kumar Singh,Arpan Kumar Kar,Yashwant Singh,Maheshkumar H. Kolekar,Sudeep Tanwar,2019-11-21 This book presents high-quality, original contributions (both theoretical and experimental) on software engineering, cloud computing, computer networks & internet technologies, artificial intelligence, information security, and database and distributed computing. It gathers papers presented at ICRIC 2019, the 2nd International Conference on Recent Innovations in Computing, which was held in Jammu, India, in March 2019. This conference series represents a targeted response to the growing need for research that reports on and assesses the practical implications of IoT and network technologies, AI and machine learning, cloud-based e-Learning and big data, security and privacy, image processing and computer vision, and next-generation computing technologies.

Innovations in Information and Communication Technologies (IICT-2020) Pradeep Kumar Singh,Zdzislaw Polkowski,Sudeep Tanwar,Sunil Kumar Pandey,Gheorghe Matei,Daniela Pirvu,2021-07-15 This edited book is comprised of original research that focuses on technological advancements for effective teaching with an emphasis on learning outcomes, ICT trends in higher education, sustainable developments and digital ecosystem in education, management and industries. The contents of the book are classified as; (i) Emerging ICT Trends in Education, Management and Innovations (ii) Digital Technologies for advancements in education, management and IT (iii) Emerging Technologies for Industries and Education, and (iv) ICT Technologies for Intelligent Applications. The book represents a useful tool for academics, researchers, industry professionals and policymakers to share and learn about the latest teaching and learning practices supported by ICT. It also covers innovative concepts applied in education, management and industries using ICT tools.

Planning Algorithms Steven Michael LaValle,2006 Written for computer scientists and engineers with interests in artificial intelligence, robotics, or control theory, this is the only book on this topic that integrates literature from several fields into a coherent source for teaching and reference in applications including robotics, computational biology, computer graphics, manufacturing, aerospace applications, and medicine.

Robotic Grasping and Manipulation Yu Sun,Joe Falco,2018-07-14 This book constitutes the refereed proceedings of the First Robotic Grasping and Manipulation Challenge, RGMC 2016, held at IROS 2016, Daejeon, South Korea, in October 2016.The 13 revised full papers presented were carefully reviewed and are describing the rules, results, competitor systems and future directions of the inaugural competition. The competition was designed to allow researchers focused on the application of robot systems to compare the performance of hand designs as well as autonomous grasping and manipulation solutions across a common set of tasks. The competition was comprised of three tracks that included hand-in-hand grasping, fully autonomous grasping, and simulation.

Robot Manipulator Control Frank L. Lewis,Darren M. Dawson,Chaouki T. Abdallah,2003-12-12 Robot Manipulator Control offers a complete survey of control systems for serial-link robot arms and acknowledges how robotic device performance hinges upon a well-developed control system. Containing over 750 essential equations, this thoroughly up-to-date Second Edition, the book explicates theoretical and mathematical requisites for controls design and summarizes current techniques in computer simulation and implementation of controllers. It also addresses procedures and issues in computed-torque, robust, adaptive, neural network, and force control. New chapters relay practical information on commercial robot manipulators and devices and cutting-edge methods in neural network control.

Interpretable Machine Learning Christoph Molnar,2020 This book is about making machine learning models and their decisions interpretable. After exploring the concepts of interpretability, you will learn about simple, interpretable models such as decision trees, decision rules and linear regression. Later chapters focus on general model-agnostic methods for interpreting black box models like feature importance and accumulated local effects and explaining individual predictions with Shapley values and LIME. All interpretation methods are explained in depth and discussed critically. How do they work under the hood? What are their strengths and

weaknesses? How can their outputs be interpreted? This book will enable you to select and correctly apply the interpretation method that is most suitable for your machine learning project.

Making Things Move DIY Mechanisms for Inventors, Hobbyists, and Artists Dustyn Roberts, 2010-12-06 Get Your Move On! In Making Things Move: DIY Mechanisms for Inventors, Hobbyists, and Artists, you'll learn how to successfully build moving mechanisms through non-technical explanations, examples, and do-it-yourself projects - from kinetic art installations to creative toys to energy-harvesting devices. Photographs, illustrations, screen shots, and images of 3D models are included for each project. This unique resource emphasizes using off-the-shelf components, readily available materials, and accessible fabrication techniques. Simple projects give you hands-on practice applying the skills covered in each chapter, and more complex projects at the end of the book incorporate topics from multiple chapters. Turn your imaginative ideas into reality with help from this practical, inventive guide. Discover how to: Find and select materials Fasten and join parts Measure force, friction, and torque Understand mechanical and electrical power, work, and energy Create and control motion Work with bearings, couplers, gears, screws, and springs Combine simple machines for work and fun Projects include: Rube Goldberg breakfast machine Mousetrap powered car DIY motor with magnet wire Motor direction and speed control Designing and fabricating spur gears Animated creations in paper An interactive rotating platform Small vertical axis wind turbine SADbot: the seasonally affected drawing robot Make Great Stuff! TAB, an imprint of McGraw-Hill Professional, is a leading publisher of DIY technology books for makers, hackers, and electronics hobbyists.

Autonomous Flying Robots Kenzo Nonami, Farid Kendoul, Satoshi Suzuki, Wei Wang, Daisuke Nakazawa, 2010-09-15 The advance in robotics has boosted the application of autonomous vehicles to perform tedious and risky tasks or to be cost-effective substitutes for their - man counterparts. Based on their working environment, a rough classification of the autonomous vehicles would include unmanned aerial vehicles (UAVs), - manned ground vehicles (UGVs), autonomous underwater vehicles (AUVs), and autonomous surface vehicles (ASVs). UAVs, UGVs, AUVs, and ASVs are called UVs (unmanned vehicles) nowadays. In recent decades, the development of - manned autonomous vehicles have been of great interest, and different kinds of autonomous vehicles have been studied and developed all over the world. In particular, UAVs have many applications in emergency situations; humans often cannot come close to a dangerous natural disaster such as an earthquake, a flood, an active volcano, or a nuclear disaster. Since the development of the first UAVs, research efforts have been focused on military applications. Recently, however, demand has arisen for UAVs such as aero-robots and flying robots that can be used in emergency situations and in industrial applications. Among the wide variety of UAVs that have been developed, small-scale HUAVs (helicopter-based UAVs) have the ability to take off and land vertically as well as the ability to cruise in flight, but their most important capability is hovering. Hovering at a point enables us to make more effective observations of a target. Furthermore, small-scale HUAVs offer the advantages of low cost and easy operation.

Intelligent Autonomous Vehicles International Federation of Automatic Control, 1993-09-06 There is an increasing range of applications in which a robot has to operate in large unstructured and uncertain environments - including military cross country missions, fire fighting, construction, nuclear plant inspections, inspecting and repairing subsea structures, assembling space stations, as well as in intelligent automobiles. Uncertainty dominates the problem domain for intelligent autonomous vehicles (IAVs) through sensing the environment and vehicle state, interpreting the data, assessing the situation, adapting to changes in the environment or tasking, replanning, navigation and piloting. IFAC, recognising the industrial, technical and economic significance of IAV research, established an International Working Party to promote research and dissemination of results in IAV systems. The IAV-93 Southampton Workshop and these resulting proceedings exemplify the vitality and significant progress made by leading IAV researchers worldwide.

Formation Control Hyo-Sung Ahn, 2019-03-29 This monograph introduces recent developments in formation control of distributed-agent systems. Eschewing the traditional concern with the dynamic characteristics of individual agents, the book proposes a treatment that studies the formation control problem in terms of interactions among agents including factors such as sensing topology, communication and actuation topologies, and computations. Keeping pace with recent technological advancements in control, communications, sensing and computation that have begun to bring the applications of distributed-systems theory out of the industrial sphere and into that of day-to-day life, this monograph provides distributed control algorithms for a group of agents that may behave together. Unlike traditional control laws that usually require measurements with respect to a global coordinate frame and communications between a centralized operation center and agents, this book provides control laws that require only relative measurements and communications between agents without interaction with a centralized operator. Since the control algorithms presented in this book do not require any global sensing and any information exchanges with a centralized operation center, they can be realized in a fully distributed way, which significantly reduces the operation and implementation costs of a group of agents. Formation Control will give both students and researchers interested in pursuing this field a good grounding on which to base their work.

Computer Vision Systems Dimitrios Tzovaras, Dimitrios Giakoumis, Markus Vincze, Antonis Argyros, 2019-11-22 This book constitutes the refereed proceedings of the 12th International Conference on Computer Vision Systems, ICVS 2019, held in Thessaloniki, Greece, in September 2019. The 72 papers presented were carefully reviewed and selected from 114 submissions. The papers are organized in the following topical sections; hardware accelerated and real time vision systems; robotic vision; vision systems applications; high-level and learning vision systems; cognitive vision systems; movement analytics and gesture recognition for human-machine collaboration in industry; cognitive and computer vision assisted systems for energy awareness and behavior analysis; and vision-enabled UAV and counter UAV technologies for surveillance and security of critical infrastructures.

Programming Robots with ROS Morgan Quigley, Brian Gerkey, William D. Smart, 2015-11-16 Chapter 3. Topics; Publishing to a Topic; Checking That Everything Works as Expected; Subscribing to a Topic; Checking That Everything Works as Expected; Latched Topics; Defining Your Own Message Types; Defining a New Message; Using Your New Message; When Should You Make a New Message Type?; Mixing Publishers and Subscribers; Summary; Chapter 4. Services; Defining a Service; Implementing a Service; Checking That Everything Works as Expected; Other Ways of Returning Values from a Service; Using a Service; Checking That Everything Works as Expected; Other Ways to

Call Services; Summary.

Introduction to AI Robotics, second edition Robin R. Murphy, 2019-10-01 A comprehensive survey of artificial intelligence algorithms and programming organization for robot systems, combining theoretical rigor and practical applications. This textbook offers a comprehensive survey of artificial intelligence (AI) algorithms and programming organization for robot systems. Readers who master the topics covered will be able to design and evaluate an artificially intelligent robot for applications involving sensing, acting, planning, and learning. A background in AI is not required; the book introduces key AI topics from all AI subdisciplines throughout the book and explains how they contribute to autonomous capabilities. This second edition is a major expansion and reorganization of the first edition, reflecting the dramatic advances made in AI over the past fifteen years. An introductory overview provides a framework for thinking about AI for robotics, distinguishing between the fundamentally different design paradigms of automation and autonomy. The book then discusses the reactive functionality of sensing and acting in AI robotics; introduces the deliberative functions most often associated with intelligence and the capability of autonomous initiative; surveys multi-robot systems and (in a new chapter) human-robot interaction; and offers a “metaview” of how to design and evaluate autonomous systems and the ethical considerations in doing so. New material covers locomotion, simultaneous localization and mapping, human-robot interaction, machine learning, and ethics. Each chapter includes exercises, and many chapters provide case studies. Endnotes point to additional reading, highlight advanced topics, and offer robot trivia.

Springer Handbook of Robotics Bruno Siciliano, Oussama Khatib, 2016-07-27 The second edition of this handbook provides a state-of-the-art overview on the various aspects in the rapidly developing field of robotics. Reaching for the human frontier, robotics is vigorously engaged in the growing challenges of new emerging domains. Interacting, exploring, and working with humans, the new generation of robots will increasingly touch people and their lives. The credible prospect of practical robots among humans is the result of the scientific endeavour of a half a century of robotic developments that established robotics as a modern scientific discipline. The ongoing vibrant expansion and strong growth of the field during the last decade has fueled this second edition of the Springer Handbook of Robotics. The first edition of the handbook soon became a landmark in robotics publishing and won the American Association of Publishers PROSE Award for Excellence in Physical Sciences & Mathematics as well as the organization’s Award for Engineering & Technology. The second edition of the handbook, edited by two internationally renowned scientists with the support of an outstanding team of seven part editors and more than 200 authors, continues to be an authoritative reference for robotics researchers, newcomers to the field, and scholars from related disciplines. The contents have been restructured to achieve four main objectives: the enlargement of foundational topics for robotics, the enlightenment of design of various types of robotic systems, the extension of the treatment on robots moving in the environment, and the enrichment of advanced robotics applications. Further to an extensive update, fifteen new chapters have been introduced on emerging topics, and a new generation of authors have joined the handbook’s team. A novel addition to the second edition is a comprehensive collection of multimedia references to more than 700 videos, which bring valuable insight into the contents. The videos can be viewed directly augmented into the text with a smartphone or tablet using a unique and specially designed app. Springer Handbook of Robotics Multimedia Extension Portal: <http://handbookofrobotics.org/>

Mathematics for Computer Science Eric Lehman, F. Thomson Leighton, Albert R. Meyer, 2017-03-08 This book covers elementary discrete mathematics for computer science and engineering. It emphasizes mathematical definitions and proofs as well as applicable methods. Topics include formal logic notation, proof methods; induction, well-ordering; sets, relations; elementary graph theory; integer congruences; asymptotic notation and growth of functions; permutations and combinations, counting principles; discrete probability. Further selected topics may also be covered, such as recursive definition and structural induction; state machines and invariants; recurrences; generating functions.

Learning for Adaptive and Reactive Robot Control Aude Billard, Sina Mirrazavi, Nadia Figueroa, 2022-02-08 Methods by which robots can learn control laws that enable real-time reactivity using dynamical systems; with applications and exercises. This book presents a wealth of machine learning techniques to make the control of robots more flexible and safe when interacting with humans. It introduces a set of control laws that enable reactivity using dynamical systems, a widely used method for solving motion-planning problems in robotics. These control approaches can replan in milliseconds to adapt to new environmental constraints and offer safe and compliant control of forces in contact. The techniques offer theoretical advantages, including convergence to a goal, non-penetration of obstacles, and passivity. The coverage of learning begins with low-level control parameters and progresses to higher-level competencies composed of combinations of skills. Learning for Adaptive and Reactive Robot Control is designed for graduate-level courses in robotics, with chapters that proceed from fundamentals to more advanced content. Techniques covered include learning from demonstration, optimization, and reinforcement learning, and using dynamical systems in learning control laws, trajectory planning, and methods for compliant and force control. Features for teaching in each chapter: applications, which range from arm manipulators to whole-body control of humanoid robots; pencil-and-paper and programming exercises; lecture videos, slides, and MATLAB code examples available on the author’s website. an eTextbook platform website offering protected material[EPS2] for instructors including solutions.

Out Of Control Kevin Kelly, 2009-04-30 Out of Control chronicles the dawn of a new era in which the machines and systems that drive our economy are so complex and autonomous as to be indistinguishable from living things.

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