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| 1. Record Nr. | UNINA990001683100403321 |
| Autore | Widtsoe, John Andreas <1872-1952> |
| Titolo | Le Dry-Farming / John A. Widtsoe |
| Pubbl/distr/stampa | Paris : Librairie agricole de la Maison rustique, 1912 |
| Edizione | [2e ed.] |
| Descrizione fisica | XXXVI, 304 p. ; 16 cm |
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| Lingua di pubblicazione | Francese |
| Formato | Materiale a stampa |
| Livello bibliografico | Monografia |
| 2. Record Nr. | UNINA9910962885403321 |
| Autore | Bullo Francesco |
| Titolo | Distributed control of robotic networks : a mathematical approach to motion coordination algorithms // Francesco Bullo, Jorge Cortes, Sonia Martinez |
| Pubbl/distr/stampa | Princeton, NJ, : Princeton University Press, 2009 |
| ISBN | 9786612458200 9786612935756 9781680158977 168015897X 9781282458208 1282458205 9781282935754 1282935755 9781400831470 1400831474 9780691141954 0691141959 |
| Edizione | [Course Book] |
| Descrizione fisica | 1 online resource (333 p.) |
| Collana | Princeton series in applied mathematics |
| Classificazione | SK 880 |
| Altri autori (Persone) | CortesJorge <1974-> MartinezSonia <1974-> |
| Disciplina | 629.8/9246 |
| Soggetti | Robotics |

Computer algorithms
Robots - Control systems

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| Lingua di pubblicazione | Inglese |
| Formato | Materiale a stampa |
| Livello bibliografico | Monografia |
| Note generali | Description based upon print version of record. |
| Nota di bibliografia | Includes bibliographical references and index. |
| Nota di contenuto | Frontmatter -- Contents -- Preface -- Chapter One. An introduction to distributed algorithms -- Chapter Two. Geometric models and optimization -- Chapter Three. Robotic network models and complexity notions -- Chapter Four. Connectivity maintenance and rendezvous -- Chapter Five. Deployment -- Chapter Six. Boundary estimation and tracking -- Bibliography -- Algorithm Index -- Subject Index -- Symbol Index |
| Sommario/riassunto | <p>This self-contained introduction to the distributed control of robotic networks offers a distinctive blend of computer science and control theory. The book presents a broad set of tools for understanding coordination algorithms, determining their correctness, and assessing their complexity; and it analyzes various cooperative strategies for tasks such as consensus, rendezvous, connectivity maintenance, deployment, and boundary estimation. The unifying theme is a formal model for robotic networks that explicitly incorporates their communication, sensing, control, and processing capabilities--a model that in turn leads to a common formal language to describe and analyze coordination algorithms. Written for first- and second-year graduate students in control and robotics, the book will also be useful to researchers in control theory, robotics, distributed algorithms, and automata theory. The book provides explanations of the basic concepts and main results, as well as numerous examples and exercises. Self-contained exposition of graph-theoretic concepts, distributed algorithms, and complexity measures for processor networks with fixed interconnection topology and for robotic networks with position-dependent interconnection topology Detailed treatment of averaging and consensus algorithms interpreted as linear iterations on synchronous networks Introduction of geometric notions such as partitions, proximity graphs, and multicenter functions Detailed treatment of motion coordination algorithms for deployment, rendezvous, connectivity maintenance, and boundary estimation</p> |