1. Record Nr. UNINA990002003080403321

Titolo	Biology / Willis H. Johnson
Pubbl/distr/stampa	New York ; Chicago : Holt, Rinebart and Winston, 1966
Edizione	[3rd ed.]
Descrizione fisica	788 p. ; 25 cm
Disciplina	574.02
Locazione	DAGEN DBV
Collocazione	61 II B.5/50 5 VI 43
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia

2. Record Nr. UNINA9910254206103321

Autore	Francis Bruce A
Titolo	Flocking and Rendezvous in Distributed Robotics / / by Bruce A. Francis, Manfredi Maggiore
Pubbl/distr/stampa	Cham : , : Springer International Publishing : , : Imprint : Springer, , 2016
ISBN	3-319-24729-8
Edizione	[1st ed. 2016.]
Descrizione fisica	1 online resource (113 p.)
Collana	SpringerBriefs in Control, Automation and Robotics, , 2192-6786
Disciplina	629.892
Soggetti	Robotics Automation Automatic control System theory Robotics and Automation Control and Systems Theory Systems Theory, Control
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.
Nota di contenuto	Introduction -- Models of Mobile Robots in the Plane -- Admissible Controls and the Robot Flocking Problem -- The Robot Rendezvous Problem: Limited Camera Range -- A Convoy Problem -- A Look into the Future: Flying Robots.
Sommario/riassunto	This brief describes the coordinated control of groups of robots using only sensory input – and no direct external commands. Furthermore, each robot employs the same local strategy, i.e., there are no leaders, and the text also deals with decentralized control, allowing for cases in which no single robot can sense all the others. One can get intuition for the problem from the natural world, for example, flocking birds. How do they achieve and maintain their flying formation? Recognizing their importance as the most basic coordination tasks for mobile robot networks, the brief details flocking and rendezvous. They are shown to be physical illustrations of emergent behaviors with global consensus arising from local interactions. The authors extend the consideration of these fundamental ideas to describe their operation in flying robots and prompt readers to pursue further research in the field. Flocking and Rendezvous in Distributed Robotics will provide graduate students a firm grounding in the subject, while also offering an authoritative reference work for more experienced workers seeking a brief but thorough treatment of an area that has rapidly gained in interest.