

1.	Record Nr.	UNINA990008346200403321
	Autore	Muller-Erzbach, Rudolf
	Titolo	Deutsches Handelsrecht / Rudolf Müller-Erzback
	Pubbl/distr/stampa	Tübingen : J. C. B. Mohr, [1928?]
	Edizione	[2. und 3. Aufl.]
	Descrizione fisica	XVI, 931 p. ; 24 cm
	Disciplina	346.43
	Locazione	FGBC
	Collocazione	VIII G 136
	Lingua di pubblicazione	Tedesco
	Formato	Materiale a stampa
	Livello bibliografico	Monografia
2.	Record Nr.	UNINA990002568970403321
	Autore	Clavel, Gilles
	Titolo	Introduzione alla programmazione / Gilles Clavel, Joelle Biondi
	Pubbl/distr/stampa	Milano : Masson, 1985
	ISBN	882140585
	Descrizione fisica	x, 259 p. ; 24 cm
	Disciplina	001
	Locazione	MAS
	Collocazione	MXXI-A-43
	Lingua di pubblicazione	Inglese
	Formato	Materiale a stampa
	Livello bibliografico	Monografia

3.	Record Nr.	UNINA990002025770403321
	Titolo	Natural enemy databank 1987 : a catalogue of natural enemies of arthropods derived from records in the CIBC natural enemy databank / comp. by J.M. Fry
	Pubbl/distr/stampa	Ascot : C.A.B., 1987
	ISBN	0-85198-653-6
	Descrizione fisica	184 p. ; 29 cm
	Disciplina	632.652
	Locazione	DAGEN
	Collocazione	61 VII B.6/60
	Lingua di pubblicazione	Inglese
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4.	Record Nr.	UNINA9910416086603321
	Autore	Chin Cheng Siong
	Titolo	Benchmark Models of Control System Design for Remotely Operated Vehicles / / by Cheng Siong Chin, Michael Wai Shing Lau
	Pubbl/distr/stampa	Singapore : , : Springer Nature Singapore : , : Imprint : Springer, , 2020
	ISBN	981-15-6511-2
	Edizione	[1st ed. 2020.]
	Descrizione fisica	1 online resource (XII, 140 p. 141 illus., 61 illus. in color.)
	Disciplina	623.82
	Soggetti	Control engineering Robotics Automation Oceanography Control, Robotics, Automation Ocean Sciences
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	Livello bibliografico	Monografia

Nota di contenuto

Introduction -- Added Mass Computation for Control of An Open-Frame Remotely-Operated Vehicle: Application using WAMIT and MATLAB -- Modeling and Testing of Hydrodynamic Damping Model for a Complex-Shaped Remotely-Operated Vehicle for Control -- Robust and Decoupled Cascaded Control System of Underwater Robotic Vehicle for Stabilization and Pipeline Tracking -- Supervisory Cascaded Controllers Design: Experiment Test on a Remotely-Operated Vehicle -- Systematic Modeling and Model-based Simulation of a Remotely-Operated Vehicle using MATLAB and Simulink -- Experimental Validation of Open-Frame ROV model for Virtual Reality Simulation and Control -- Robust Genetic Algorithm and Fuzzy Inference Mechanism Embedded in Sliding-Mode Controller for Uncertain Underwater Robot.

Sommario/riassunto

This book is intended to meet the needs of those who seek to develop control systems for ROVs when there is no model available during the initial design stage. The modeling, simulation and application of marine vehicles like underwater robotic vehicles (URVs) are multidisciplinary, and combine mathematical aspects from various engineering disciplines. URVs such as remotely operated vehicle (ROVs) are used for a wide range of applications such as exploring the extreme depths of our ocean, where a hard-wired link is still required. Most ROVs operate in extreme environments with uncertainties in the model prior to control system design. However, the method involved extensive testing before the system model could be used for any control actions. It has been found that the range of error can be extensive and uncertain in actual, continuously varying conditions. Hence, it is important to address the problem of reliance on model testing using different modeling approaches. In this book, approaches such as WAMIT, ANSYS-CFX, STAR CCM+, MATLAB and Simulink are used to model parameters for ROVs. A few benchmark models are provided, allowing researchers and students to explore and test different control schemes. Given its scope, the book offers a valuable reference guide for postgraduate and undergraduate students engaged in modeling and simulation for ROV control. .
