1. Record Nr. UNINA990008378530403321

Autore	Woods, May
Titolo	Glass houses : a history of greenhouses, orangeries and conservatories / May Woods and Arete Swartz Warren
Pubbl/distr/stampa	New York : Rizzoli, c1988
ISBN	0-8478-0906-4
Descrizione fisica	216 p. : in gran parte ill. ; 27 cm
Altri autori (Persone)	Swartz Warren, Arete
Disciplina	728.9
Locazione	DCATA
Collocazione	301019
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	Include bibliografia e indice

2. Record Nr. UNINA9910557743603321

Autore	Tomazic Simon
Titolo	Indoor Positioning and Navigation
Pubbl/distr/stampa	Basel, Switzerland, : MDPI - Multidisciplinary Digital Publishing Institute, 2021
Descrizione fisica	1 online resource (350 p.)
Soggetti	Energy industries & utilities Technology: general issues
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Sommario/riassunto	In recent years, rapid development in robotics, mobile, and communication technologies has encouraged many studies in the field of localization and navigation in indoor environments. An accurate localization system that can operate in an indoor environment has considerable practical value, because it can be built into autonomous mobile systems or a personal navigation system on a smartphone for guiding people through airports, shopping malls, museums and other public institutions, etc. Such a system would be particularly useful for blind people. Modern smartphones are equipped with numerous sensors (such as inertial sensors, cameras, and barometers) and communication modules (such as WiFi, Bluetooth, NFC, LTE/5G, and UWB capabilities), which enable the implementation of various localization algorithms, namely, visual localization, inertial navigation system, and radio localization. For the mapping of indoor environments and localization of autonomous mobile sysems, LIDAR sensors are also frequently used in addition to smartphone sensors. Visual localization and inertial navigation systems are sensitive to external disturbances; therefore, sensor fusion approaches can be used for the implementation of robust localization algorithms. These have to be optimized in order to be computationally efficient, which is essential for real-time processing and low energy consumption on a smartphone

or robot.