1. Record Nr. UNINA990009815060403321

Autore	Caiani, Manuela
Titolo	Web nero [Risorsa elettronica] : organizzazioni di estrema destra e Internet / Manuela Caiani, Linda Parenti
Pubbl/distr/stampa	Bologna : Società editrice il Mulino, 2013
ISBN	9788815314260
Altri autori (Persone)	Parenti, Linda
Disciplina	322.42
Lingua di pubblicazione	Italiano
Formato	Risorsa elettronica
Livello bibliografico	Monografia

2. Record Nr. UNINA9910464543603321

Autore	Wang Zhan
Titolo	Simultaneous localization and mapping [[electronic resource]] : exactly sparse information filters / / Zhan Wang, Shoudong Huang, Gamini Dissanayake
Pubbl/distr/stampa	Singapore ; ; Hackensack, N.J., : World Scientific, c2011
ISBN	1-283-43379-6 9786613433794 981-4350-32-X
Descrizione fisica	1 online resource (208 p.)
Collana	New frontiers in robotics ; ; v. 3
Altri autori (Persone)	HuangShoudong <1969-> DissanayakeGamini
Disciplina	629.892637
Soggetti	Mobile robots Robots - Control systems Sparse matrices Robotics Mappings (Mathematics) Electronic books.
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 (p. 180-194).
Nota di contenuto	Contents; Preface; Acknowledgments; Chapter 1 Introduction; 1.1 The SLAM Problem and Its Applications; 1.1.1 Description of the SLAM Problem; 1.1.2 Applications of SLAM; 1.2 Summary of SLAM Approaches; 1.2.1 EKF/EIF based SLAM Approaches; 1.2.2 Other SLAM Approaches; 1.3 Key Properties of SLAM; 1.3.1 Observability; 1.3.2 EKF SLAM Convergence; 1.3.3 EKF SLAM Consistency; 1.4 Motivation; 1.5 Book Overview; Chapter 2 Sparse Information Filters in SLAM; 2.1 Information Matrix in the Full SLAM Formulation; 2.2 Information Matrix in the Conventional EIF SLAM Formulation 2.3 Meaning of Zero Off-diagonal Elements in Information Matrix2.4 Conditions for Achieving Exact Sparseness; 2.5 Strategies for Achieving Exact Sparseness; 2.5.1 Decoupling Localization and Mapping; 2.5.2 Using Local Submaps; 2.5.3 Combining Decoupling and Submaps; 2.6 Important Practical Issues in EIF SLAM; 2.7 Summary; Chapter 3 Decoupling Localization and Mapping; 3.1 The D-SLAM Algorithm; 3.1.1 Extracting Map Information from Observations; 3.1.2 Key Idea of D-SLAM; 3.1.3 Mapping; 3.1.4 Localization; 3.2 Structure of the Information Matrix in D-SLAM 3.3 Efficient State and Covariance Recovery3.3.1 Recovery Using the Preconditioned Conjugated Gradient (PCG) Method; 3.3.2 Recovery Using Complete Cholesky Factorization; 3.4 Implementation Issues; 3.4.1 Admissible Measurements; 3.4.2 Data Association; 3.5 Computer Simulations; 3.6 Experimental Evaluation; 3.6.1 Experiment in a Small Environment; 3.6.2 Experiment Using the Victoria Park Dataset; 3.7 Computational Complexity; 3.7.1 Storage; 3.7.2 Localization; 3.7.3 Mapping; 3.7.4 State and Covariance Recovery; 3.8 Consistency of D-SLAM; 3.9 Bibliographical Remarks; 3.10 Summary Chapter 4 D-SLAM Local Map Joining Filter4.1 Structure of D-SLAM Local Map Joining Filter; 4.1.1 State Vectors; 4.1.2 Relative Information Relating Feature Locations; 4.1.3 Combining Local Maps Using Relative Information; 4.2 Obtaining Relative Location Information in Local Maps; 4.2.1 Generating a Local Map; 4.2.2 Obtaining Relative Location Information in the Local Map; 4.3 Global Map Update; 4.3.1 Measurement Model; 4.3.2 Updating the Global Map; 4.3.3 Sparse Information Matrix; 4.4 Implementation Issues; 4.4.1 Robot Localization; 4.4.2 Data Association; 4.4.3 State and Covariance Recovery 4.4.4 When to Start a New Local Map4.5 Computational Complexity; 4.5.1 Storage; 4.5.2 Local Map Construction; 4.5.3 Global Map Update; 4.5.4 Rescheduling the Computational Effort; 4.6 Computer Simulations; 4.6.1 Simulation in a Small Area; 4.6.2 Simulation in a Large Area; 4.7 Experimental Evaluation; 4.8 Bibliographical Remarks; 4.9 Summary; Chapter 5 Sparse Local Submap Joining Filter; 5.1 Structure of Sparse Local Submap Joining Filter; 5.1.1 Input to SLSJF - Local Maps; 5.1.2 Output of SLSJF - One Global Map; 5.2 Fusing Local Maps into the Global Map 5.2.1 Adding XG(k+1)s into the Global Map
Sommario/riassunto	Simultaneous localization and mapping (SLAM) is a process where an autonomous vehicle builds a map of an unknown environment while concurrently generating an estimate for its location. This book is concerned with computationally efficient solutions to the large scale SLAM problems using exactly sparse Extended Information Filters (EIF). The invaluable book also provides a comprehensive theoretical analysis of the properties of the information matrix in EIF-based algorithms for

SLAM. Three exactly sparse information filters for SLAM are described in detail, together with two efficient and exact methods for recovering the state vector and the covariance matrix. Proposed algorithms are extensively evaluated both in simulation and through experiments.

3. Record Nr. UNISA996389051303316

Autore	Person in command of the fleet
Titolo	An exact relation of the several engagements and actions of His Majesties fleet, under the command of His Highness Prince Rupert [[electronic resource]] : And of all circumstances concerning this somers expedition, anno 1673. / / Written by a person in command in the fleet
Pubbl/distr/stampa	London, : Printed for J.B., anno Dom.1673
Descrizione fisica	[2], 21 p
Soggetti	Great Britain History Charles II, 1660-1685 Early works to 1800 Great Britain History, Naval Stuarts, 1603-1714 Early works to 1800
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	In this setting t.p. has "somers"; C2r fifth line from bottom has "four a clock." Reproduction of original in: Henry E. Huntington Library and Art Gallery.
Sommario/riassunto	eebo-0113