

1. Record Nr.	UNINA9910466774903321
Titolo	30 millennia of sculpture // Joseph Manca [and four others]
Pubbl/distr/stampa	New York : , : Parkstone International, , 2012 ©2012
ISBN	1-68325-362-0
Descrizione fisica	1 online resource (780 pages) : color illustrations, photographs
Disciplina	730.9
Soggetti	Sculpture - History Electronic books.
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	Includes index.
2. Record Nr.	UNINA9910140860803321
Autore	Tsourdos Antonios
Titolo	Cooperative path planning of unmanned aerial vehicles [[electronic resource] /] / Antonios Tsourdos, Brian White and Madhavan Shanmugavel
Pubbl/distr/stampa	Chichester, West Sussex, U.K. ; ; Hoboken, N.J., : Wiley, 2011
ISBN	0-470-97464-8 0-470-97463-X 0-470-97520-2
Descrizione fisica	1 online resource (216 p.)
Collana	Aerospace Series ; ; v.32
Altri autori (Persone)	WhiteBrian <1947 June 6-> ShanmugavelMadhavan
Disciplina	623.7469 629.132/5 629.1325
Soggetti	Drone aircraft - Automatic control Guidance systems (Flight) Airplanes - Piloting - Mathematics Airplanes - Piloting - Planning Airways - Mathematical models

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	Cooperative Path Planning of Unmanned Aerial Vehicles; Contents; About the Authors; Series Preface; Preface; Acknowledgements; List of Figures; List of Tables; Nomenclature; 1 Introduction; 2 Path Planning in Two Dimensions; 3 Path Planning in Three Dimensions; 4 Collision Avoidance; 5 Path-Following Guidance; 6 Path Planning for Multiple UAVs; Appendix A Differential Geometry; Appendix B Pythagorean Hodograph; Index
Sommario/riassunto	An invaluable addition to the literature on UAV guidance and cooperative control, Cooperative Path Planning of Unmanned Aerial Vehicles is a dedicated, practical guide to computational path planning for UAVs. One of the key issues facing future development of UAVs is path planning: it is vital that swarm UAVs/ MAVs can cooperate together in a coordinated manner, obeying a pre-planned course but able to react to their environment by communicating and cooperating. An optimized path is necessary in order to ensure a UAV completes its mission efficiently, safely, and successfully. Foc