

1. Record Nr.	UNINA9910299886803321
Titolo	Field and Service Robotics : Results of the 11th International Conference // edited by Marco Hutter, Roland Siegwart
Pubbl/distr/stampa	Cham : , : Springer International Publishing : , : Imprint : Springer, , 2018
ISBN	3-319-67361-0
Edizione	[1st ed. 2018.]
Descrizione fisica	1 online resource (XV, 715 p. 382 illus.)
Collana	Springer Proceedings in Advanced Robotics, , 2511-1256 ; ; 5
Disciplina	629.892
Soggetti	Robotics Automation Artificial intelligence Robotics and Automation Artificial Intelligence
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Nota di bibliografia	Includes bibliographical references.
Nota di contenuto	Part 1: Control.- Part 2: Computer Vision -- Part 3: Inspection -- Part 4: Machine Learning -- Part 5: Mapping -- Part 6: Navigation and Planning -- Part 7: Systems and Tools.
Sommario/riassunto	This book contains the proceedings of the 11th FSR (Field and Service Robotics), which is the leading single-track conference on applications of robotics in challenging environments. This conference was held in Zurich, Switzerland from 12-15 September 2017. The book contains 45 full-length, peer-reviewed papers organized into a variety of topics: Control, Computer Vision, Inspection, Machine Learning, Mapping, Navigation and Planning, and Systems and Tools. The goal of the book and the conference is to report and encourage the development and experimental evaluation of field and service robots, and to generate a vibrant exchange and discussion in the community. Field robots are non-factory robots, typically mobile, that operate in complex and dynamic environments: on the ground (Earth or other planets), under the ground, underwater, in the air or in space. Service robots are those that work closely with humans to help them with their lives. The first FSR was held in Canberra, Australia, in 1997. Since that first meeting,

FSR has been held roughly every two years, cycling through Asia, Americas, and Europe.
