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Titolo	Knowing how to know [[electronic resource]] : fieldwork and the ethnographic present / / edited by Narmala Halstead, Eric Hirsch and Judith Okely
Pubbl/distr/stampa	New York, : Berghahn Books, 2008
ISBN	1-84545-477-4 1-282-62704-X 9786612627040 0-85745-069-7
Descrizione fisica	1 online resource (216 p.)
Collana	EASA series ; ; 9
Altri autori (Persone)	HalsteadNarmala HirschEric <1956-> OkelyJudith <1941->
Disciplina	305.800723
Soggetti	Ethnology - Fieldwork Ethnology - Authorship Ethnology - Philosophy Ethnologists - Attitudes 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 and index.
Nota di contenuto	Title page-Knowing How to Know; Contents; Introduction; Chapter 1-Knowing, Not knowing, knowing anew; Chapter 2-The Transformation of Indigenous Knowledge into Anthropological Knowledge; Chapter 3-Knowing without notes; Chapter 4-To know the dancer; Chapter 5-Knowledge as gifts of self and other; Chapter 6-Knowledge from the body; Chapter 7-What is sacred about that pile of stones at Mt. Tendong?; Chapter 8-Learning to see; Chapter 9-Rescuing theory from the nation; Notes on contributors; Index
Sommario/riassunto	This volume examines some crucial issues in the conduct of fieldwork and ethnography and provides new insights into the problems of constructing anthropological knowledge. How is anthropological knowledge created from fieldwork, whose knowledge is this, who

	determines what is of significance in any ethnographic context, and how is the fieldsite extended in both time and place?. Nine anthropologists examine these problems, drawing on diverse case studies. These range from the dilemmas of the religious refashioning of the ethnographer in contemporary Indonesia to the embodied knowledge of ballet

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Titolo	Cooperative control of distributed multi-agent systems [[electronic resource] /] / edited by Jeff S. Shamma
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ISBN	1-281-31911-2 9786611319113 0-470-72420-X 0-470-72419-6
Descrizione fisica	1 online resource (453 p.)
Altri autori (Persone)	ShammaJeff S
Disciplina	003.5 003/.5
Soggetti	Distributed artificial intelligence Control theory Cooperation - Mathematics Distributed databases Electronic data processing - Distributed processing 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 and index.
Nota di contenuto	Cooperative Control of Distributed Multi-Agent Systems; Contents; List of Contributors; Preface; Part I Introduction; 1 Dimensions of cooperative control; 1.1 Why cooperative control?; 1.1.1 Motivation; 1.1.2 Illustrative example: command and control of networked vehicles; 1.2 Dimensions of cooperative control; 1.2.1 Distributed control and

computation; 1.2.2 Adversarial interactions; 1.2.3 Uncertain evolution; 1.2.4 Complexity management; 1.3 Future directions; Acknowledgements; References; Part II Distributed Control and Computation
2 Design of behavior of swarms: From flocking to data fusion using microfilter networks2.1 Introduction; 2.2 Consensus problems; 2.3 Flocking behavior for distributed coverage; 2.3.1 Collective potential of flocks; 2.3.2 Distributed flocking algorithms; 2.3.3 Stability analysis for flocking motion; 2.3.4 Simulations of flocking; 2.4 Microfilter networks for cooperative data fusion; Acknowledgements; References; 3 Connectivity and convergence of formations; 3.1 Introduction; 3.2 Problem formulation; 3.3 Algebraic graph theory
3.4 Stability of vehicle formations in the case of time-invariant communication3.4.1 Formation hierarchy; 3.5 Stability of vehicle formations in the case of time-variant communication; 3.6 Stabilizing feedback for the time-variant communication case; 3.7 Graph connectivity and stability of vehicle formations; 3.8 Conclusion; Acknowledgements; References; 4 Distributed receding horizon control: stability via move suppression; 4.1 Introduction; 4.2 System description and objective; 4.3 Distributed receding horizon control; 4.4 Feasibility and stability analysis; 4.5 Conclusion; Acknowledgement References5 Distributed predictive control: synthesis, stability and feasibility; 5.1 Introduction; 5.2 Problem formulation; 5.3 Distributed MPC scheme; 5.4 DMPC stability analysis; 5.4.1 Individual value functions as Lyapunov functions; 5.4.2 Generalization to arbitrary number of nodes and graph; 5.4.3 Exchange of information; 5.4.4 Stability analysis for heterogeneous unconstrained LTI subsystems; 5.5 Distributed design for identical unconstrained LTI subsystems; 5.5.1 LQR properties for dynamically decoupled systems; 5.5.2 Distributed LQR design; 5.6 Ensuring feasibility
5.6.1 Robust constraint fulfillment5.6.2 Review of methodologies; 5.7 Conclusion; References; 6 Task assignment for mobile agents; 6.1 Introduction; 6.2 Background; 6.2.1 Primal and dual problems; 6.2.2 Auction algorithm; 6.3 Problem statement; 6.3.1 Feasible and optimal vehicle trajectories; 6.3.2 Benefit functions; 6.4 Assignment algorithm and results; 6.4.1 Assumptions; 6.4.2 Motion control for a distributed auction; 6.4.3 Assignment algorithm termination; 6.4.4 Optimality bounds; 6.4.5 Early task completion; 6.5 Simulations; 6.5.1 Effects of delays; 6.5.2 Effects of bidding increment
6.5.3 Early task completions

Sommario/riassunto

The paradigm of 'multi-agent' cooperative control is the challenge frontier for new control system application domains, and as a research area it has experienced a considerable increase in activity in recent years. This volume, the result of a UCLA collaborative project with Caltech, Cornell and MIT, presents cutting edge results in terms of the "dimensions" of cooperative control from leading researchers worldwide. This dimensional decomposition allows the reader to assess the multi-faceted landscape of cooperative control. Cooperative Control of Distributed Multi-Agent Systems is organized