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Autore	Pomares Jorge
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Sommario/riassunto	Visual servoing is a well-known approach to guide robots using visual information. Image processing, robotics, and control theory are combined in order to control the motion of a robot depending on the visual information extracted from the images captured by one or several cameras. With respect to vision issues, a number of issues are currently being addressed by ongoing research, such as the use of different types of image features (or different types of cameras such as RGBD cameras), image processing at high velocity, and convergence properties. As shown in this book, the use of new control schemes allows the system to behave more robustly, efficiently, or compliantly, with fewer delays. Related issues such as optimal and robust approaches, direct control, path tracking, or sensor fusion are also addressed. Additionally, we can currently find visual servoing systems being applied in a number of different domains. This book considers various aspects of visual servoing systems, such as the design of new strategies for their application to parallel robots, mobile manipulators, teleoperation, and the application of this type of control system in new areas.