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Nota di contenuto	Intro -- Preface -- An Overview of Optoelectronic Devices in Robotic Systems -- Acknowledgments -- Contents -- Editors and Contributors -- About the Authors -- Contributors -- Abbreviations -- 3D Model-Based Tracking of Puppet in Depth Images for the Dynamic Video-Mapping of Its Suit -- 1 Introduction -- 1.1 Motivation -- 1.2 Related Works -- 1.3 Real-Time Estimation of Every Puppet DoF -- 1.4 Chapter Outline -- 2 Video-Mapping Setup Modeling and Calibration -- 2.1 Geometrical Modeling -- 2.2 Calibration -- 2.2.1 RGBD Camera Calibration -- 2.2.2 Video-Projector Calibration -- 3 Silhouette-Based Visual Tracking -- 3.1 3D Model Silhouette Computation -- 3.2 Silhouette Samples Tracking -- 3.3 Pose Computation -- 3.4 Joint Angles Computation -- 3.5 Solving the 3D Pose and Joint Angles Together -- 4 Puppet Dynamic Video-Mapping Demonstrations -- 4.1 Hardware Setup and Software -- 4.2 Video-Mapping -- 4.3 Dynamic Video-Mapping -- 4.3.1 Rigid Puppet -- 4.3.2 Articulated Puppet -- 4.3.3 Video -- 5 Discussion -- 6 Conclusion -- References -- Aerial Robotics for Precision Agriculture: Weeds Detection Through UAV and Machine Vision -- 1 Introduction -- 2 Monitoring Scenario -- 3 Aerial Robotic System -- 3.1 UAV -- 3.2 RGB, Multispectral, and Hyperspectral Cameras and Laser Scanners -- 4 Computer Vision --

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