

1. Record Nr.	UNINA9910713070303321
Autore	Schroeder Roy A.
Titolo	Trends in polychlorinated biphenyl concentrations in Hudson River water five years after elimination of point sources // by Roy A. Schroeder and Charles R. Barnes
Pubbl/distr/stampa	Albany, New York : , : U.S. Geological Survey, , 1983
Descrizione fisica	1 online resource (v, 28 pages) : illustrations, maps
Collana	Water-resources investigations report ; ; 83-4206
Soggetti	Polychlorinated biphenyls - Environmental aspects Drinking water - Contamination - Hudson River (N.Y. and N.J.) Water - Pollution - Hudson River (N.Y. and N.J.) Polychlorinated biphenyls Water - Pollution Hudson River (N.Y. and N.J.) United States Hudson River
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	"Prepared in cooperation with the New York State Department of Environmental Conservation."
Nota di bibliografia	Includes bibliographical references (pages 24-28).

2. Record Nr.	UNINA9910996493603321
Autore	Yang Chenguang
Titolo	Advanced Teleoperation and Robot Learning for Dexterous Manipulation // by Chenguang Yang, Zhenyu Lu, Ning Wang
Pubbl/distr/stampa	Cham : , : Springer Nature Switzerland : , : Imprint : Springer, , 2025
ISBN	3-031-78501-0
Edizione	[1st ed. 2025.]
Descrizione fisica	1 online resource (XIV, 200 p. 108 illus., 105 illus. in color.)
Collana	Springer Tracts in Advanced Robotics, , 1610-742X ; ; 160
Disciplina	629.8
Soggetti	Automatic control Robotics Automation Computational intelligence Control, Robotics, Automation Control and Systems Theory Computational Intelligence
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Nota di contenuto	Part I: Single-Leader-Dual-Follower Teleoperation for Cooperative Manipulation -- Motion Regulation Solutions for Holding and Moving Objects in Single-Leader-Dual-Follower Teleoperation -- Single-Leader-Dual-Follower Cooperative Manipulation of Deformable Objects -- Part II: Integrated Autonomous Learning and Control Framework -- A Small Opening Workspace Control Strategy for Redundant Manipulator Based on Remote Center of Movement Method -- Motor Learning and Generalization using Broad Learning Adaptive Neural Control -- Hybrid Learning and Control using Improved Dynamical Movement Primitive and Adaptive Neural Network Control -- Part III: Bio-inspired Autonomous Learning for Dexterous Manipulations -- A Constrained DMP Framework for Robot Skills Learning and Generalization from Human Demonstrations- Incremental Motor Skill Learning and Generalization From Human Dynamic Reactions Based on Dynamic Movement Primitive and Fuzzy Logic System -- Motor Learning and Generalization using Broad Learning Adaptive Neural Control.

## Sommario/riassunto

This book offers an in-depth exploration of the interdisciplinary field of dexterous robotic manipulation, focusing on advanced methods that enable robots to autonomously learn, adapt, and perform a variety of tasks. It covers key topics such as teleoperation systems, advanced control frameworks, and bio-inspired autonomous learning. The book stands out by providing a comprehensive examination of both the technical and theoretical aspects of dexterous manipulation, with a particular emphasis on integrating advanced control and autonomous learning. The book is primarily aimed at researchers, engineers, and graduate students in the fields of robotics, artificial intelligence, and control systems. It is particularly useful for those interested in robotic manipulation, autonomous learning, and bio-inspired systems. The detailed technical explanations and cutting-edge research make it an essential resource for professionals seeking to push the boundaries of robotic dexterous manipulation. The book's practical applications make it relevant for many real-world manipulation scenarios, including healthcare and manufacturing.

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