1. Record Nr. UNINA9910713736603321

Titolo	Estimated use of water in North Dakota in 1985 and trends during 1960-85 / / by Edwin A. Wesolowski ; prepared by U.S. Department of the Interior, U.S. Geological Survey in cooperation with North Dakota State Water Commission
Pubbl/distr/stampa	[Bismarck, N.D.] : , : [U.S. Geological Survey], , 1991
Descrizione fisica	1 online resource (7 maps on 1 sheet) : color
Collana	Water-resources investigations report ; ; 89-4003
Soggetti	Water use - North Dakota Water consumption - North Dakota Water-supply - North Dakota Water consumption Water-supply Water use Maps. North Dakota
Lingua di pubblicazione	Inglese
Formato	Materiale cartografico a stampa
Livello bibliografico	Monografia
Note generali	Divided into sections on supply, demand, and distribution.
Nota di bibliografia	Includes text, table, diagram, eighteen graphs, and bibliographical references.

2. Record Nr. UNINA9910741179703321

Autore	Abdessameud Abdelkader
Titolo	Motion coordination for VTOL unmanned aerial vehicles : attitude synchronisation and formation control / / Abdelkader Abdessameud, Abdelhamid Tayebi
Pubbl/distr/stampa	New York, : Springer, 2013
ISBN	1-4471-5094-5
Edizione	[1st ed. 2013.]
Descrizione fisica	1 online resource (xv, 182 pages) : illustrations (some color)
Collana	Advances in industrial control
Altri autori (Persone)	TayebiAbdelhamid
Disciplina	623 629.132/6 629.1326
Soggetti	Drone aircraft - Control systems Aeronautics
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	"ISSN: 1430-9491."
Nota di bibliografia	Includes bibliographical references and index.
Nota di contenuto	Background and Preliminaries -- Mathematical Models of Flying Vehicles -- Attitude Synchronization -- Attitude Synchronization with Communication Delays -- Global Trajectory Tracking of VTOL UAVs -- Formation Control of VTOL UAVs -- Formation Control with Communication Delays.
Sommario/riassunto	Motion Coordination for VTOL Unmanned Aerial Vehicles develops new control design techniques for the distributed coordination of a team of autonomous unmanned aerial vehicles. In particular, it provides new control design approaches for the attitude synchronization of a formation of rigid body systems. In addition, by integrating new control design techniques with some concepts from nonlinear control theory and multi-agent systems, it presents a new theoretical framework for the formation control of a class of under-actuated aerial vehicles capable of vertical take-off and landing. Several practical problems related to the systems' inputs, states measurements, and restrictions on the interconnection topology between the aerial vehicles in the team are addressed. Worked examples with sufficient details and simulation results are provided to illustrate the applicability and effectiveness of the theoretical results discussed in the book. The

material presented is primarily intended for researchers and industrial engineers from robotics, control engineering and aerospace communities. It also serves as a complementary reading for graduate students involved in research related to flying robotics, aerospace, control of under-actuated systems, and nonlinear control theory.