1.	Record Nr.	UNINA9910827582003321
	Titolo	Flight formation control / / edited by Jose A. Guerrero, Rogelio Lozano
	Pubbl/distr/stampa	London, : ISTE Ltd. Hoboken, N.J., : John Wiley & Sons, 2012
	ISBN	1-118-38719-8 1-299-18849-4 1-118-56325-5 1-118-56322-0
	Edizione	[1st ed.]
	Descrizione fisica	1 online resource (342 p.)
	Collana	ISTE
	Altri autori (Persone)	GuerreroJose A <1977-> (Jose Alfredo) LozanoR <1954-> (Rogelio)
	Disciplina	629.132/6
	Soggetti	Airplanes - Control systems Airplanes - Automatic control Drone aircraft - Control systems Drone aircraft - Automatic control Stability of airplanes
	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	Cover; Flight Formation Control; Title Page; Copyright Page; Table of Contents; Chapter 1. Introduction; 1.1. Motivation; 1.2. Historical background; 1.2.1. Aviation history; 1.2.2. Evolution of UAVs; 1.2.3. UAV classification; 1.3. Flight control; 1.4. Flight formation control; 1.4.1. Multiple-input and multiple-output; 1.4.2. Leader/follower; 1.4.3. Virtual structure; 1.4.4. Behavior-based control; 1.4.5. Passivity- based control; 1.5. Outline of the book; 1.6. Bibliography; Chapter 2. Theoretical Preliminaries; 2.1. Passivity; 2.2. Graph theory; 2.3. Robustness problems 2.3.1. Representation of the parametric uncertainty2.3.2. Families of polynomials; 2.4. Bibliography; Chapter 3. Multiagent Coordination Strategies; 3.1. Introduction; 3.2. Controllability and observability of interconnections; 3.2.1. Cyclic topology; 3.2.2. Chain topology: input and output on agent 1; 3.2.3. Chain topology: input and output on

	agent 2; 3.2.4. Eigenvalues and eigenvectors of the system; 3.2.5. General case; 3.2.6. The cyclic topology in the general case; 3.2.6.1. Observability; 3.2.6.2. Controllability; 3.2.7. The chain topology in the general case; 3.2.7.1. Controllability; 3.2.8.2. Observability; 3.2.9. Simple configurations that are either non-controllable or non-observable; 3.2.9.1. Example 1; 3.2.9.2. Example 2; 3.2.9.3. Example 3; 3.2.9.4. Example 4; 3.2.9.5. Example 5; 3.3. Formation leader tracking; 3.3.1. Formation leader tracking in the general case; 3.3.2. Observer design; 3.3.3. Simulations; 3.4. Time-varying trajectory tracking; 3.5. Linear high-order multiagent consensus; 3.5.1. Trajectory-tracking control; 3.6. Conclusion; 3.7. Bibliography Chapter 4. Robust Control Design of Multiagent Systems with Parametric Uncertainty4.1. Introduction; 4.2. Robust control design; 4.3. Robust stability analysis; 4.3.1. Robust strict positive realness; 4.3.2. Application to multiagent systems; 4.5.1. Cyclic topology; 4.5.2. Chain topology; 4.5.3. Balanced graph topology; 4.6. Conclusions; 5.1. Summary; 5.2. Introduction 5.3. Problem formulation5.4. Adaptive controlled synchronization on strongly connected graph; 5.4.1. Delay-free synchronization, 5.4.2. Synchronization with time delay; 5.5. Robust controlled synchronization on strongly connected graph; 5.4.1. Delay-free synchronization; 5.4.2. Synchronization with time delay; 5.6. Numerical examples; 5.6.1. Adaptive tracking algorithm; 5.6.2. Robust tracking algorithm; 5.6.3. Disturbances; 5.7. Conclusions; 5.8. Appendix; 5.8.1. Robotic system; 5.8.2. Graph theory; 5.9. Bibliography; Chapter 6. Modeling and Control of Mini UAV; 6.1. Introduction 6.2. General model
Sommario/riassunto	In the last decade the development and control of Unmanned Aerial Vehicles (UAVs) has attracted a lot of interest. Both researchers and companies have a growing interest in improving this type of vehicle given their many civilian and military applications. This book presents the state of the art in the area of UAV Flight Formation. The coordination and robust consensus approaches are presented in detail as well as formation flight control strategies which are validated in experimental platforms. It aims at helping students and academics alike to better understand what coordination and