1. Record Nr. UNINA9910965100803321

Autore	Zoe L, Devlin
Titolo	Death embodied : Archaeological approaches to the treatment of the corpse
Pubbl/distr/stampa	Havertown, : Oxbow Books, 2015
ISBN	9781782979463 1782979468 9781782979449 1782979441
Descrizione fisica	1 online resource (181 p.)
Collana	Studies in Funerary Archaeology ; ; v.9
Altri autori (Persone)	Emma-Jayne, Graham
Disciplina	930.1
Soggetti	Burial - History - To 1500 Human remains (Archaeology) - History - Social aspects - To 1500 Dead - History - Social aspects - To 1500 Death - History - To 1500 Burial Funeral rites and ceremonies, Ancient Excavations (Archaeology) Social archaeology Archaeology History & Archaeology Human remains (Archaeology) - Social aspects - History - To 1500 Dead - Social aspects - History - To 1500
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	Description based upon print version of record.
Nota di contenuto	1. Introduction: Embodying death in archaeology; 2. Neither Fish nor Fowl: Burial practices between inhumationand cremation; 3. Corporeal Concerns: The role of the body in the transformationof Roman mortuary practices; 4. '(Un)touched by decay': Anglo-Saxon encounters with dead bodies; 5. Funerary and Post-depositional Body Treatments at the Middle Anglo-SaxonCemetery Winnall II: Norm, variety - and deviance?; 6. The Burnt, the Whole and the Broken: Funerary variabilityin the Linearbandkeramik; 7. Practices of Ritual

Marginalisation in Late Prehistoric Veneto:Evidence from the field

8. Prehistoric Maltese Death: Democratic theatre or elite democracy?

Sommario/riassunto

In April 1485, a marble sarcophagus was found on the outskirts of Rome. It contained the remains of a young Roman woman so well-preserved that she appeared to have only just died and the sarcophagus was placed on public view, attracting great crowds. Such a find reminds us of the power of the dead body to evoke in the minds of living people, be they contemporary (survivors or mourners) or distanced from the remains by time, a range of emotions and physical responses, ranging from fascination to fear, and from curiosity to disgust. Archaeological interpretations of burial remains can often suggest that the skeletons which we uncover, and therefore usually associate with past funerary practices, were what was actually deposited in graves, rather than articulated corpses. The choices made by past communities or individuals about how to cope with a dead body in all of its dynamic and constituent forms, and whether there was reason to treat it in a manner that singled it out (positively or negatively) as different from other human corpses, provide the stimulus for this volume. The nine papers provide a series of theoretically informed, but not constrained, case studies which focus predominantly on the corporeal body in death. The aims are to take account of the active presence of dynamic material bodies at the heart of funerary events and to explore the questions that might be asked about their treatment; to explore ways of putting fleshed bodies back into our discussions of burials and mortuary treatment, as well as interpreting the meaning of these activities in relation to the bodies of both deceased and survivors; and to combine the insights that body-centered analysis can produce to contribute to a more nuanced understanding of the role of the body, living and dead, in past cultures.

2. Record Nr. UNINA9910755077603321

Autore	Subramanian Rajesh
Titolo	Build Autonomous Mobile Robot from Scratch using ROS : Simulation and Hardware / / by Rajesh Subramanian
Pubbl/distr/stampa	Berkeley, CA : , : Apress : , : Imprint : Apress, , 2023
ISBN	9781484296455 1484296451
Edizione	[1st ed. 2023.]
Descrizione fisica	1 online resource (579 pages)
Collana	Maker Innovations Series, , 2948-2550
Disciplina	006.3
Soggetti	Makerspaces Robotics Maker
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	Includes index.
Nota di contenuto	Chapter 1: Introduction to Robotics Part I -- Chapter 2: Introduction to Robotics Part II -- Chapter 3: Setting Up Workstation for Simulation -- Chapter 4: ROS Framework -- Chapter 5: Robot Simulation & Visualization -- Chapter 6: Arduino and ROS -- Chapter 7: Simulating Bumblebot: A Simple Two-Wheeled Robot -- Chapter 8: Building Bumblebot in Hardware -- Chapter 9: Additional Sensors and Sensor Fusion in Bumblebot -- Chapter 10: Bonus Materials: Web Interface and Autonomous Docking Using Bumblebot.
Sommario/riassunto	Start from scratch and build a variety of features for autonomous mobile robots both in simulation and hardware. This book will show you how to simulate an autonomous mobile robot using ROS and then develop its hardware implementation. You'll start by gaining an understanding of the basic theoretical concepts underlying the development of autonomous robots, including history, mathematics, electronics, mechanical aspects, 3D modelling, 3D printing, Linux, and programming. In subsequent chapters, you will learn how to describe kinematics, simulate and visualize the robot, how to interface Arduino with ROS, tele-operate the robot, perform mapping, autonomous navigation, add additional sensors, sensor fusion, laser scan matching, web interface, and more. Not only will you learn theoretical aspects,

you’ll also review the hardware realization of mobile robots. Projects start with a very basic two-wheeled mobile robot and progress to complex features such as mapping, navigation, sensor fusion, autodocking, and web interface. Upon completing this book, you’ll have incorporated important robot algorithms including SLAM, Path Finding, Localization, and Kalman Filters – and you will be ready to start designing and building your own autonomous robots. You will: Design and build your customized physical robot with autonomous navigation capability Create a map of your house using the robot’s lidar scanner Command the robot to go to any accessible location on the map Interact with the robot using a mobile app, joystick, keyboard, push-button, or remote computer Monitor robot updates via LCD, a mobile app, sound, and status LEDs Automate delivery of small payloads and return to home base Utilize autodocking to home base for battery charging Leverage sensor fusion to improve accuracy Interface with the robot via the Web to monitor and control it remotely.