1.	Record Nr.	UNINA9911047655303321
	Autore	Li Qiang
	Titolo	AI Enabled Robotic Loco-Manipulation : Proceedings of the CLAWAR 2025 Conference, Volume 2 / / edited by Qiang Li, Ming Xie, Mohammad Osman Tokhi, Manuel F. Silva
	Pubbl/distr/stampa	Cham : , : Springer Nature Switzerland : , : Imprint : Springer, , 2025
	ISBN	3-032-09427-5
	Edizione	[1st ed. 2025.]
	Descrizione fisica	1 online resource (343 pages)
	Collana	Lecture Notes in Networks and Systems, , 2367-3389 ; ; 1666
	Disciplina	629.8
	Soggetti	Automatic control Robotics Automation Computational intelligence Control, Robotics, Automation Computational Intelligence
	Lingua di pubblicazione	Inglese
	Formato	Materiale a stampa
	Livello bibliografico	Monografia
	Sommario/riassunto	This book is the proceedings of the 28th International conference on Climbing and Walking Robots and the Support Technologies for Mobile Machines. The conference is organized by CLAWAR Association in collaboration with the Shenzhen Technology University, China, during September 5–7, 2025. This book provides latest research and development findings and state-of-the-art insights into the mobile robotics and associated technologies in a diverse range of application scenarios, within the framework of "AI enabled robotic loco-manipulation". The topics covered include Assistive Robotics and Support Technologies, Bio-Inspired Robotics for Dynamic Locomotion and Manipulation in Challenging Environments, Progress, Application and Trends of Multimodal Locomotion Robots, and Tactile Sensing and Haptic Technologies in Touch-driven Robotics. The intended readership includes participants of CLAWAR 2025 conference, worldwide researchers, scientists, and educators in the areas of robotics and related topics. This book is also a good source for courses in Robotics

and Automation, Control Engineering, Mechanical Engineering, and Mechatronics.