1. Record Nr. UNISA990003120280203316

Autore	ROSSETTI, William Michael
Titolo	Diario della confraternita preraffaellita / William Michael Rossetti ; introduzione, traduzione e note di Manuela D'Amore
Pubbl/distr/stampa	Lugano : Lumières internationales, copyr. 2005
ISBN	88-6067-003-9
Descrizione fisica	XI, 246 p. ; 24 cm
Collana	Ottocento e dintorni ; 2
Disciplina	759.2
Soggetti	Preraffaelliti
Collocazione	XIII.5. 255
Lingua di pubblicazione	Italiano
Formato	Materiale a stampa
Livello bibliografico	Monografia

2. Record Nr. UNINA9910786162603321

Titolo	Robotic navigation and mapping with radar / / Martin Adams [and others]
Pubbl/distr/stampa	Boston ; , : Artech House, , ©2012 [Piscataqay, New Jersey] : , : IEEE Xplore, , [2012]
ISBN	1-60807-483-8
Descrizione fisica	1 online resource (377 p.)
Altri autori (Persone)	AdamsMartin David
Disciplina	629.045
Soggetti	Mobile robots - Automatic control Autonomous robots Robots - Control systems Radar in navigation
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	Introduction -- Fundamentals of radar and robotic navigation. A brief overview of radar fundamentals -- An introduction to detection theory -- Robotic navigation and mapping -- Radar modeling and scan integration. Predicting and simulating FMCW radar measurements -- Reducing detection errors and noise with multiple radar scans -- Robotic mapping with known vehicle location. Grid-based robotic mapping with detection likelihood filtering -- Feature-based robotic mapping with random finite sets -- Simultaneous localization and mapping. Radar-based SLAM with random finite sets -- x-band radar-based SLAM in an off-shore environment.
Sommario/riassunto	Focusing on autonomous robotic applications, this cutting-edge resource offers a practical treatment of short-range processing for reliable object detection at ground level. This book demonstrates probabilistic radar models and detection algorithms specifically for robotic vehicles on land and at sea, in coastal environments. It examines grid-based robotic mapping with radar, based on measurement likelihood estimation. Moreover, this book reformulates the feature-based robotic mapping and simultaneous localization and map building (SLAM) problems, so that detection, as well as spatial,

uncertainty can be incorporated in a principled manner.