

1. Record Nr.	UNISA996395399503316
Autore	Coke Edward, Sir, <1552-1634.>
Titolo	A booke of entries [[electronic resource] ] : containing perfect and approued presidents of counts, declarations, informations, pleints, inditements, barres, replications, reioynders, pleadings, processes, continuances, essoines, issues, defaults, departure in despite of the court, demurrers, trialls, iudgements, executions, and all other matters and proceedings (in effect) concerning the practique part of the laws of England, in actions reall, personall, and mixt, and in appeales; necessarie to be knowne, and of excellent vse for the moderne practise of the law, many of them contayning matters in law and points of great learning: and none of them euer imprinted heretofore. Collected and published for the common good and benefit of all the studious and learned professors of the laws of England
Pubbl/distr/stampa	London, : Printed [by Adam Islip] for the Societie of Stationers, anno Dom. 1614
Descrizione fisica	[10], 713, [11] leaves
Soggetti	Pleading - Great Britain Forms (Law) - Great Britain
Lingua di pubblicazione	Latino
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	Prefaces signed: Edvv. Coke. Mostly in Latin. Edited by Thomas Jones, Common Serjeant of London?. At foot of title: Cum priuilegio. Printer's name from STC. The first leaf and the last leaf are blank. Reproduction of the original in the British Library.
Sommario/riassunto	eebo-0018

2. Record Nr.	UNINA9910766894303321
Autore	Pan Huihui
Titolo	Robust Environmental Perception and Reliability Control for Intelligent Vehicles // by Huihui Pan, Jue Wang, Xinghu Yu, Weichao Sun, Huijun Gao
Pubbl/distr/stampa	Singapore : , : Springer Nature Singapore : , : Imprint : Springer, , 2024
ISBN	9789819977901 9819977908
Edizione	[1st ed. 2024.]
Descrizione fisica	1 online resource (308 pages)
Collana	Recent Advancements in Connected Autonomous Vehicle Technologies, , 2731-0035 ; ; 4
Disciplina	359.8205
Soggetti	Automotive engineering Automatic control Computational intelligence Automotive Engineering Control and Systems Theory Computational Intelligence
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Nota di bibliografia	Includes bibliographical references.
Nota di contenuto	Chapter 1. Background -- Chapter 2. Robust Environmental Perception of Multi-Sensor Data Fusion -- Chapter 3. Robust Environmental Perception of Monocular 3D Object Detection -- Chapter 4. Robust Environmental Perception of Semantic Segmentation -- Chapter 5. Robust Environmental Perception of Trajectory Prediction -- Chapter 6. Robust Environmental Perception of Multi-object Tracking -- Chapter 7. Reliability Control of Intelligent Vehicles -- References.
Sommario/riassunto	This book presents the most recent state-of-the-art algorithms on robust environmental perception and reliability control for intelligent vehicle systems. By integrating object detection, semantic segmentation, trajectory prediction, multi-object tracking, multi-sensor fusion, and reliability control in a systematic way, this book is aimed at guaranteeing that intelligent vehicles can run safely in complex road traffic scenes. Adopts the multi-sensor data fusion-based neural networks to environmental perception fault tolerance

algorithms, solving the problem of perception reliability when some sensors fail by using data redundancy. Presents the camera-based monocular approach to implement the robust perception tasks, which introduces sequential feature association and depth hint augmentation, and introduces seven adaptive methods. Proposes efficient and robust semantic segmentation of traffic scenes through real-time deepdual-resolution networks and representation separation of vision transformers. Focuses on trajectory prediction and proposes phased and progressive trajectory prediction methods that is more consistent with human psychological characteristics, which is able to take both social interactions and personal intentions into account. Puts forward methods based on conditional random field and multi-task segmentation learning to solve the robust multi-object tracking problem for environment perception in autonomous vehicle scenarios. Presents the novel reliability control strategies of intelligent vehicles to optimize the dynamic tracking performance and investigates the completely unknown autonomous vehicle tracking issues with actuator faults.

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