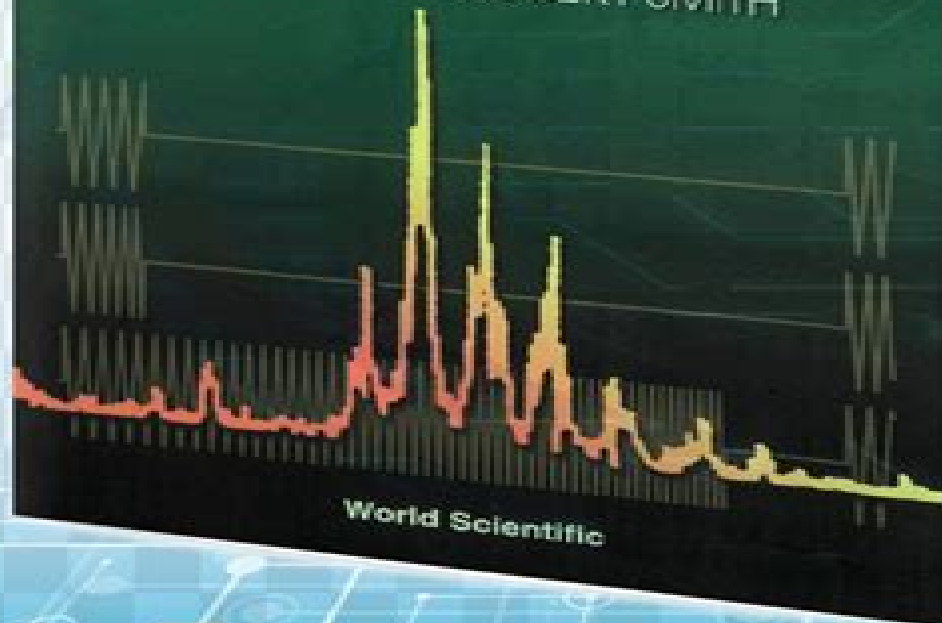


World Scientific Series in Robotics and Intelligent Systems – Vol. 26

ACTIVE SENSORS FOR LOCAL PLANNING IN MOBILE ROBOTICS

PENELOPE PROBERT SMITH



Active Sensors For Local Planning In Mobile Robotics

Jiyuan Zhang



Active Sensors For Local Planning In Mobile Robotics:

Active Sensors For Local Planning In Mobile Robotics Penelope Probert Smith, 2001-12-05 This book describes recent work on active sensors for mobile robots. An active sensor interacts with its surroundings to supply data on demand for a particular function, gathering and abstracting information according to need rather than acting as a generic data gatherer. Details of the physical operation are hidden. The book deals mainly with active range sensors which provide rapid information for local planning, describing extraction of two dimensional features such as lines, corners and cylinders to reconstruct a plan of a building. It is structured according to the physical principles of the sensors, since to a large extent these determine the function of the sensors and the methods of processing. Recent work using sonar, optoelectronic sensors and radar is described. Sections on vision and on sensor management develop the idea of software adaptation for efficient operation in a changing environment.

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Contents: The Mapping and Localisation Problem, Perception at Millimetre Wavelengths, Advanced Sonar, Principles of Operation and Interpretation, Smooth and Rough Target Modelling, Examples in Mapping and Texture Classification, Sonar Systems, A Biological Perspective, Map Building from Range Data, Using Mathematical Morphology, Millimetre Wave Radar for Robotics, Optoelectronic Range Sensors, AMCW LIDAR, Range Acquisition, Extracting Lines and Curves from Optoelectronic Range Data, Active Vision for Mobile Robot Navigation, Strategies for Active Sensor Management.

Readership: Graduate students and final year undergraduate students in electrical and electronic engineering systems and knowledge robotics, image processing and artificial intelligence.

Mobile Robotics in Healthcare Nikos Katevas, 2001 The text presents the conclusions of four years joint work of 12 European laboratories on mobile robotics technology for healthcare services. The book bridges the human factors and the demands of real life applications to the achievements of the robotics technology. It is organized in 15 chapters analyzing topics covering all the related fields and including but not limited to: user application requirements, human machine interfacing, mobile robots and mobile manipulators, control architectures, navigation and sensing strategies and robot smart building interconnection. It also provides technical details and hints to the reader on how to address real life problems. The book also performs a historical review and includes

an overview of the contemporary developments worldwide **Wavelets In Soft Computing (Second Edition)** Marc Thuillard, 2022-09-09 The comprehensive compendium furnishes a quick and efficient entry point to many multiresolution techniques and facilitates the transition from an idea into a real project It focuses on methods combining several soft computing techniques fuzzy logic neural networks genetic algorithms in a multiresolution framework Illustrated with numerous vivid examples this useful volume gives the reader the necessary theoretical background to decide which methods suit his/her needs New materials and applications for multiresolution analysis are added including notable research topics such as deep learning graphs and network analysis **Fuzzy Decision Making in Modeling and Control** João M. C. Sousa, Uzey Kaymak, 2002 Decision making and control are two fields with distinct methods for solving problems and yet they are closely related This book bridges the gap between decision making and control in the field of fuzzy decisions and fuzzy control and discusses various ways in which fuzzy decision making methods can be applied to systems modeling and control Fuzzy decision making is a powerful paradigm for dealing with human expert knowledge when one is designing fuzzy model based controllers The combination of fuzzy decision making and fuzzy control in this book can lead to novel control schemes that improve the existing controllers in various ways The following applications of fuzzy decision making methods for designing control systems are considered Fuzzy decision making for enhancing fuzzy modeling The values of important parameters in fuzzy modeling algorithms are selected by using fuzzy decision making Fuzzy decision making for designing signal based fuzzy controllers The controller mappings and the defuzzification steps can be obtained by decision making methods Fuzzy design and performance specifications in model based control Fuzzy constraints and fuzzy goals are used Design of model based controllers combined with fuzzy decision modules Human operator experience is incorporated for the performance specification in model based control The advantages of bringing together fuzzy control and fuzzy decision making are shown with multiple examples from real and simulated control systems *Evolutionary Robotics: From Algorithms To Implementations* Ling-feng Wang, Kay Chen Tan, Chee-meng Chew, 2006-07-17 This invaluable book comprehensively describes evolutionary robotics and computational intelligence and how different computational intelligence techniques are applied to robotic system design It embraces the most widely used evolutionary approaches with their merits and drawbacks presents some related experiments for robotic behavior evolution and the results achieved and shows promising future research directions Clarity of explanation is emphasized such that a modest knowledge of basic evolutionary computation digital circuits and engineering design will suffice for a thorough understanding of the material The book is ideally suited to computer scientists practitioners and researchers keen on computational intelligence techniques especially the evolutionary algorithms in autonomous robotics at both the hardware and software levels *Mobile Robots Navigation* Alejandra Barrera, 2010-03-01 Mobile robots navigation includes different interrelated activities i perception as obtaining and interpreting sensory information ii exploration as the strategy that guides the robot to select the next direction to go iii

mapping involving the construction of a spatial representation by using the sensory information perceived iv localization as the strategy to estimate the robot position within the spatial map v path planning as the strategy to find a path towards a goal location being optimal or not and vi path execution where motor actions are determined and adapted to environmental changes The book addresses those activities by integrating results from the research work of several authors all over the world Research cases are documented in 32 chapters organized within 7 categories next described

Modelling and Planning for Sensor Based Intelligent Robot Systems Horst Bunke,Takeo Kanade,Hartmut Noltemeier,1995 This edited and reviewed volume consists of papers that were originally presented at a workshop in the Scientific Center at Schloss Dagstuhl Germany It gives an overview of the field and presents the latest developments in the areas of modeling and planning for sensor based robots The particular topics addressed include active vision sensor fusion environment modeling motion planning robot navigation distributed control architectures reactive behavior and others

Vision-Based Mobile Robot Control and Path Planning Algorithms in Obstacle Environments Using Type-2 Fuzzy Logic Mahmut Dirik,Oscar Castillo,Fatih Kocamaz,2021-03-01 The book includes topics such as path planning avoiding obstacles following the path go to goal control localization and visual based motion control The theoretical concepts are illustrated with a developed control architecture with soft computing and artificial intelligence methods The proposed vision based motion control strategy involves three stages The first stage consists of the overhead camera calibration and the configuration of the working environment The second stage consists of a path planning strategy using several traditional path planning algorithms and proposed planning algorithm The third stage consists of the path tracking process using previously developed Gauss and Decision Tree control approaches and the proposed Type 1 and Type 2 controllers Two kinematic structures are utilized to acquire the input values of controllers These are Triangle Shape Based Controller Design which was previously developed and Distance Based Triangle Structure that is used for the first time in conducted experiments Four different control algorithms Type 1 fuzzy logic Type 2 Fuzzy Logic Decision Tree Control and Gaussian Control have been used in overall system design The developed system includes several modules that simplify characterizing the motion control of the robot and ensure that it maintains a safe distance without colliding with any obstacles on the way to the target The topics of the book are extremely relevant in many areas of research as well as in education in courses in computer science electrical and mechanical engineering and in mathematics at the graduate and undergraduate levels

State Estimation, Planning, and Behavior Selection Under Uncertainty for Autonomous Robotic Exploration in Dynamic Environments Georgios Lidoris,2011 Front cover Titelseite Impressum Foreword Abstract Zusammenfassung Contents 1 Introduction 1 1 Uncertainty in Real World Robotics 1 2 The Autonomous City Explorer Robot 1 3 Contributions and Thesis Outline 2 Simultaneous Localization Mapping and Tracking of Moving Objects 2 1 Robot Motion 2 1 1 Velocity Motion Model 2 1 2 Odometry Motion Model 2 2 Map Representations 2 2 1 Feature based representations 2 2 2 Occupancy Grid Maps 2 3

Simultaneous Localization And Mapping 2 3 1 EKF SLAM 2 3 2 Rao Blackwellized Grid based SLAM 2 4 Moving Object Tracking with Incrementally Constructed Maps 2 4 1 Conditional Particle Filters 2 4 2 Data Association 2 5 Experimental Results 2 6 Summary 3 Autonomous Robotic Exploration with Active Sensing 3 1 Related Work 3 2 Information Based Gaze Direction Planning for SLAM 3 2 1 Measuring Information 3 2 2 Planning Algorithm 3 3 Combined Trajectory Planning and Gaze Direction Control 3 3 1 Gaze Direction Control 3 3 2 Motion Planning 3 4 Results 3 4 1 Gaze Direction Planning 3 4 2 Combined Approach 3 5 Conclusion 4 Bayesian Framework for State Estimation and Behavior Selection 4 1 Related Work 4 2 Bayesian Framework 4 2 1 Prediction 4 2 2 Correction Step 4 2 3 Estimation of Behavior Probabilities 4 3 Application to Autonomous Robotic Exploration 4 3 1 System Behavior Description 4 3 2 Behavior Selection 4 3 3 Behavior Selection Model 4 4 Experimental Results 4 5 Conclusion 5 Learning Probabilistic Behavior Models from Humans 5 1 Related Work 5 2 Overview of the Proposed Learning Scheme 5 3 Support Vector Machines 5 3 1 Multi Class Support Vector Machines 5 3 2 Probability Estimates for Multi Class Support Vector Machines 5 4 Training the Classifier

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web v velocity the speed with which the wave propagates in a medium usually constant since speed times time gives distance traveled we can say the velocity of the wave

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web 1 v yrt m a constant for the particular gas r universal gas constant m molar mass kg mol t temperature measured in kelvin the measured speed of sound at

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web eq 1 in order to determine the velocity we have to set up a vibration in the medium determine the frequency and wavelength and calculate the velocity of propagation from

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