

Aníbal Ollero Iván Maza (Eds.)

Multiple Heterogeneous Unmanned Aerial Vehicles



Gregory S. Chirikjian, Howie
Choset, Marco Morales, Todd Murphey

Multiple Heterogeneous Unmanned Aerial Vehicles Aníbal Ollero, Iván Maza, 2007-10-25 Aerial robots can be considered as an evolution of the Unmanned Aerial Vehicles UAVs This book provides a guite complete overview of issues related to aerial robotics addressing problems ranging from flight control to terrain perception and mission planning and execution The major challenges and potentials of heterogeneous UAVs are comprehensively explored It builds on the results of the European project COMETS and highlights a number of key research topics in the area of UAV development including communication perception teleoperation and decision making The monograph emphasizes the current state of technology the existing problems and potentialities of systems consisting of multiple UAVs which are heterogeneous in view of the different characteristics of the aerial vehicles the different on board payloads and the different on board information processing capabilities. The book also examines potential applications of UAVs and details a relevant application case forest fire detection and monitoring Selected papers from the 2nd International Symposium on UAVs, Reno, U.S.A. June 8-10, 2009 Kimon P. Valavanis, Randal Beard, Paul Oh, Aníbal Ollero, Leslie A. Piegl, Hayong Shin, 2011-04-11 In the last decade signi cant changes have occurred in the eld of vehicle motion planning and for UAVs in particular UAV motion planning is especially dif cult due to several complexities not considered by earlier planning strategies the creased importance of differential constraints atmospheric turbulence which makes it impossible to follow a pre-computed plan precisely uncertainty in the vehicle state and limited knowledge about the environment due to limited sensor capabilities These differences have motivated the increased use of feedback and other control engineering techniques for motion planning The lack of exact algorithms for these problems and difficulty inherent in characterizing approximation algorithms makes it impractical to determine algorithm time complexity completeness and even soundness This gap has not yet been addressed by statistical characterization of experimental performance of algorithms and benchmarking Because of this overall lack of knowledge it is dif cult to design a guidance system let alone choose the algorithm Throughout this paper we keep in mind some of the general characteristics and requirements pertaining to UAVs A UAV is typically modeled as having velocity and acceleration constraints and potentially the higher order differential constraints associated with the equations of motion and the objective is to guide the vehicle towards a goal through an obstacle eld A UAV guidance problem is typically characterized by a three dimensional problem space limited information about the environment on board sensors with limited range speed and acceleration constraints and uncertainty in vehicle state and sensor data Unmanned Aircraft Systems Kimon P. Valavanis, Paul Oh, Les A. Piegl, 2008-12-21 Unmanned Aircraft Systems UAS have seen unprecedented levels of growth during the last decade in both military and civilian domains It is anticipated that civilian applications will be dominant in the future although there are still barriers to be overcome and technical challenges to be met Integrating UAS into for example civilian space navigation autonomy see detect and avoid systems smart designs system integration vision based navigation

and training to name but a few areas will be of prime importance in the near future This special volume is the outcome of research presented at the International Symposium on Unmanned Aerial Vehicles held in Orlando Florida USA from June 23 25 2008 and presents state of the art findings on topics such as UAS operations and integration into the national airspace system UAS navigation and control micro mini small UAVs UAS simulation testbeds and frameworks UAS research platforms and applications UAS applications This book aims at serving as a guide tool on UAS for engineers and practitioners academics government agencies and industry Previously published in the Journal of Intelligent and Robotic Systems 54 1 3 2009 Geolocation of RF Signals Ilir Progri, 2011-01-15 Geolocation of RF Signals Principles and Simulations offers an overview of the best practices and innovative techniques in the art and science of geolocation over the last twenty years It covers all research and development aspects including theoretical analysis RF signals geolocation techniques key block diagrams and practical principle simulation examples in the frequency band from 100 MHz to 18 GHz or even 60 GHz Starting with RF signals the book progressively examines various signal bands such as VLF LF MF HF VHF UHF L S C X Ku and K and the corresponding geolocation requirements per band and per application to achieve required performance objectives of up to 00 precision Part II follows a step by step approach of RF geolocation techniques and concludes with notes on state of the art geolocation designs as well as advanced features found in signal generator instruments Drawing upon years of practical experience and using numerous examples and illustrative applications Ilir Progri provides a comprehensive introduction to Geolocation of RF Signals and includes hands on real world labs and applications using MATLAB in the areas of RF signals specifications RF geolocation distributed wireless communications networks and RF geolocation Geolocation of RF Signals Principles and Simulations will be of interest to government agency program managers industry professionals and engineers academic researchers faculty and graduate students who are interested in or currently designing developing and deploying innovative geolocation of RF Signal systems Advances in Visual Computing George Bebis, Richard Boyle, Bahram Parvin, Darko Koracin, Ioannis Pavlidis, Rogerio Feris, Tim McGraw, Mark Elendt, Regis Kopper, Eric Ragan, Zhao Ye, Gunther Weber, 2015-12-17 The two volume set LNCS 9474 and LNCS 9475 constitutes the refereed proceedings of the 11th International Symposium on Visual Computing ISVC 2015 held in Las Vegas NV USA in December 2015 The 115 revised full papers and 35 poster papers presented in this book were carefully reviewed and selected from 260 submissions The papers are organized in topical sections Part I LNCS 9474 comprises computational bioimaging computer graphics motion and tracking segmentation recognition visualization mapping modeling and surface reconstruction advancing autonomy for aerial robotics medical imaging virtual reality observing humans spectral imaging and processing intelligent transportation systems visual perception and robotic systems Part II LNCS 9475 applications 3D computer vision computer graphics segmentation biometrics pattern recognition recognition and virtual reality Robotics and Cognitive Approaches to **Spatial Mapping** Margaret E. Jefferies, Wai-Kiang Yeap, 2008-01-10 This important work is an attempt to synthesize two

areas that need to be treated in tandem The book brings together the fields of robot spatial mapping and cognitive spatial mapping which share some common core problems One would expect some cross fertilization of research between the two areas to have occurred yet this has begun only recently There are now signs that some synthesis is happening so this work is a timely one for students and engineers in robotics Algorithmic Foundations of Robotics VIII Gregory S. Chirikjian, Howie Choset, Marco Morales, Todd Murphey, 2010-02-04 This book contains selected contributions to WAFR the highly competitive meeting on the algorithmic foundations of robotics They address the unique combination of questions that the design and analysis of robot algorithms inspires Search and Rescue Robotics Multiple Authors, 2017-08-23 In the event of large crises earthquakes typhoons floods a primordial task of the fire and rescue services is the search for human survivors on the incident site This is a complex and dangerous task which too often leads to loss of lives among the human crisis managers themselves This book explains how unmanned search can be added to the toolkit of the search and rescue workers offering a valuable tool to save human lives and to speed up the search and rescue process The introduction of robotic tools in the world of search and rescue is not straightforward due to the fact that the search and rescue context is extremely technology unfriendly meaning that very robust solutions which can be deployed extremely quickly are required Multiple research projects across the world are tackling this problem and in this book a special focus is placed on showcasing the results of the European Union ICARUS project on this subject The ICARUS project proposes to equip first responders with a comprehensive and integrated set of unmanned search and rescue tools to increase the situational awareness of human crisis managers so that more work can be done in a shorter amount of time The ICARUS tools consist of assistive unmanned air ground and sea vehicles equipped with victim detection sensors. The unmanned vehicles collaborate as a coordinated team communicating via ad hoc cognitive radio networking To ensure optimal human robot collaboration these tools are seamlessly integrated into the command and control equipment of the human crisis managers and a set of training and support tools is provided to them in order to learn to use the ICARUS system The research leading to these results has received funding from the European Community's Seventh Framework Programme FP7 2007 2013 under grant agreement number 285417 The publishing of this book was funded by the EC FP7 Post Grant Open Access Pilot programme

Experimental Robotics Oussama Khatib, Vijay Kumar, Daniela Rus, 2008-01-30 At the dawn of the new millennium robotics is undergoing a major transformation in scope and dimension From a largely dominant industrial focus robotics is rapidly expanding into the challenges of unstructured environments Interacting with assi ing serving and exploring with humans the emerging robots will increasingly touch people and their lives The goal of the new series of Springer Tracts in Advanced Robotics STAR is to bring in a timely fashion the latest advances and developments in robotics on the basis of their significance and quality It is our hope that the wider dissemination of research developments will stimulate more exchanges and collaborations among the research community and contribute to further advancement of this rapidly growing field Since

its inception wanted by my STAR Co Editor Oussama Khatib some twenty years ago the International Symposium on Experimental Robotics ISER was p lished by Springer Since the two past editions ISER has found a more suitable home under STAR together with other thematic symposia devoted to excellence in robotics research **Robot 2019: Fourth**Iberian Robotics Conference Manuel F. Silva, José Luís Lima, Luís Paulo Reis, Alberto Sanfeliu, Danilo Tardioli, 2019-11-19

This book gathers a selection of papers presented at ROBOT 2019 the Fourth Iberian Robotics Conference held in Porto Portugal on November 20th 22nd 2019 ROBOT 2019 is part of a series of conferences jointly organized by the SPR Sociedade Portuguesa de Rob tica Portuguese Society for Robotics and SEIDROB Sociedad Espa ola para la Investigaci n y Desarrollo en Rob tica Spanish Society for Research and Development in Robotics ROBOT 2019 built upon several previous successful events including three biannual workshops and the three previous installments of the Iberian Robotics Conference and chiefly focused on presenting the latest findings and applications in robotics from the Iberian Peninsula although the event was also open to research and researchers from other countries The event featured five plenary talks on state of the art topics and 16 special sessions plus a main general robotics track In total after a stringent review process 112 high quality papers written by authors from 24 countries were selected for publication

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