Reinforcement Learning For Autonomous Quadrotor Helicopter | f445d5c451ab8a14a7a1b7143b6998ea

Proceedings of the Future Technologies Conference (FTC) 2020, Volume 2Intelligent Systems: Models and ApplicationsFrom Motor Learning to Interaction Learning in RobotsRobotics, Vision and Control2018 IEEE Third International Conference on Data Science in CyberspaceModelling and Simulation for Autonomous Systems2020 Innovations in Intelligent Systems and Applications Conference (ASYU)2019 IEEE 2nd International Conference on Automation, Electronics and Electrical Engineering (AUTEEE)Congress on Intelligent SystemsQuadcopter Stabilization with Neural NetworkIntelligent Autonomous Systems 12Unmanned Aerial SystemsAutonomous Control of Unmanned Aerial VehiclesAerial ManipulationInnovation in Wind Turbine DesignRobot ShapingAutonomous Flying RobotsIntroduction to Autonomous Mobile RobotsExperimental Robotics IXFrom Bioinspired Systems and Biomedical Applications to Machine LearningMobile Intelligent Autonomous SystemsSoft Computing and Signal ProcessingRecent Advances in Information and Communication Technology 2015Drones in Smart-CitiesLifelong Machine LearningExperimental RoboticsIntelligent Autonomous Systems 15Emergent Trends in Robotics and Intelligent SystemsROS Robotics By ExampleRobot Operating System (ROS)Autonomous Navigation in Dynamic EnvironmentsGuided Autonomy for Quadcopter PhotographyDigital Twin TechnologyDeep Learning in Computer VisionPattern RecognitionSliding Mode Control in Electro-Mechanical SystemsDeep LearningProceedings of 2019 Chinese Intelligent Systems ConferenceFrontiers of Intelligent Autonomous SystemsProceedings of the 4th International Conference on Electrical Engineering and Control Applications

Proceedings of the Future Technologies Conference (FTC) 2020, Volume 2

Going beyond the traditional field of robotics to include other mobile vehicles, this reference and "recipe book" describes important theoretical concepts, techniques, and applications that can be used to build truly mobile intelligent autonomous systems (MIAS). With the infusion of neural networks, fuzzy logic, and genetic algorithm paradigms for MIAS, it blends modeling, sensors, control, estimation, optimization, signal processing, and heuristic methods in MIAS and robotics, and includes examples and applications throughout. Offering a comprehensive view of important topics, it helps readers understand the subject from a system-theoretic and practical point of view.

Intelligent Systems: Models and Applications

2019 IEEE 2nd International Conference on Automation, Electronics and Electrical Engineering (AUTEE 2019) will be held in Shenyang during November 22 24, 2019 The aim as well as objective of AUTEEE 2019 is to present the latest research and results of scientists working in the field related to Automation, Electronics and Electrical Engineering topics This conference provides opportunities for the delegates to exchange new ideas and application through face to face discussions, to establish business or research relations and to find global partners for future collaborations AUTEEE 2019 will be an International Forum for those who wish to present their projects and innovations, having also the opportunity to discuss the main aspects and the latest results in the field of Education and Research It focuses on both theory and applications mainly covering the topics of Automation, Electronics and Electrical Engineering

From Motor Learning to Interaction Learning in Robots

Apply Sliding Mode Theory to Solve Control Problems Interest in SMC has grown rapidly since the first edition of this book was published. This second edition includes new results that have been achieved in SMC throughout the past decade relating to both control design methodology and applications. In that time, Sliding Mode Control (SMC) has continued to gain increasing importance as a universal design tool for the robust control of linear and nonlinear electro-mechanical systems. Its strengths result from its simple, flexible, and highly cost-effective approach to design and implementation. Most importantly, SMC promotes inherent order reduction and allows for the direct incorporation of robustness against system uncertainties and disturbances. These qualities lead to dramatic improvements in stability and help enable the design of high-performance control systems at low cost. Written by three of the most respected experts in the field, including one of its originators, this updated edition of Sliding Mode Control in Electro-Mechanical Systems reflects developments in the field over the past decade. It builds on the solid fundamentals presented in the first edition to promote a deeper understanding of the conventional SMC methodology, and it examines new design principles in order to broaden the application potential of SMC. SMC is particularly useful for the design of electromechanical systems because of its discontinuous structure. In fact, where the hardware of many electromechanical systems (such as electric motors) prescribes discontinuous inputs, SMC becomes the natural choice for direct implementation. This book provides a unique combination of theory, implementation issues, and examples of real-life applications reflective of the authors' own industry-leading work in the development of robotics, automobiles, and other technological breakthroughs.

Robotics, Vision and Control

The author has maintained two open-source MATLAB Toolboxes for more than 10 years: one for robotics and one for vision. The key strength of the Toolboxes provide a set of tools that allow the user to work with real problems, not trivial examples. For the student the book makes the algorithms accessible, the Toolbox code can be read to gain understanding, and the examples illustrate how it can be used —instant gratification in just a couple of lines of MATLAB code. The code can also be the starting point for new work, for researchers or students, by writing programs based on Toolbox functions, or modifying the Toolbox code itself. The purpose of this book is to expand on the tutorial material provided with the toolboxes, add many more examples, and to weave this into a narrative that covers robotics and computer vision separately and together. The author shows how complex problems can be decomposed and solved using just a few simple lines of code, and hopefully to inspire up and coming researchers. The topics covered are guided by the real problems observed over many years as a practitioner of both robotics and computer vision. It is written in a light but informative style, it is easy to read and absorb, and includes a lot of Matlab examples and figures. The book is a real walk through the fundamentals of robot kinematics, dynamics and joint level control, then camera models, image processing, feature extraction and epipolar geometry, and bring it all together in a visual servo system. Additional material is provided at http://www.petercorke.com/RVC

2018 IEEE Third International Conference on Data Science in Cyberspace

This book presents the latest advances and research achievements in the fields of autonomous robots and intelligent systems, presented at the IAS-15 conference, held in Baden-Baden, Germany, in June 2018. It brings together contributions from researchers, engineers and practitioners from all over the world on the main trends of robotics: navigation, path planning, robot vision, human detection, and robot design – as well as a wide range of applications. This installment of the conference reflects the rise of machine learning and deep learning in the robotics field, as employed in a variety of applications and systems. All contributions were selected using a rigorous peer-review process to ensure their scientific quality. The series of biennial IAS conferences was started in 1986: since then, it has become an essential venue for the robotics community.

Modelling and Simulation for Autonomous Systems

Lifelong Machine Learning, Second Edition is an introduction to an advanced machine learning paradigm that continuously learns by accumulating past knowledge that it then uses in future learning and problem solving. In contrast, the current dominant machine learning paradigm learns in isolation: given a training dataset, it runs a machine learning algorithm on the dataset to produce a model that is then used in its intended application. It makes no attempt to retain the learned knowledge and use it in subsequent learning. Unlike this isolated system, humans learn effectively with only a few examples precisely because our learning is very knowledge-driven: the knowledge learned in the past helps us learn new things with little data or effort. Lifelong learning aims to emulate this capability, because without it, an AI system cannot be considered truly intelligent. Research in lifelong learning has developed significantly in the relatively short time since the first edition of this book was published. The purpose of this second edition is to expand the definition of lifelong learning, update the content of several chapters, and add a new chapter about continual learning in deep neural networks—which has been actively researched over the past two or three years. A few chapters have also been reorganized to make each of them more coherent for the reader. Moreover, the authors want to propose a unified framework for the research area. Currently, there are several research topics in machine learning that are closely related to lifelong learning—most notably, multi-task learning, transfer learning, and meta-learning—because they also employ the idea of knowledge sharing and transfer. This book brings all these topics under one roof and discusses their similarities and differences. Its goal is to introduce this emerging machine learning paradigm and present a comprehensive survey and review of the important research results and latest ideas in the area. This book is thus suitable for students, researchers, and practitioners who are interested in machine learning, data mining, natural language processing, or pattern recognition. Lecturers can readily use the book for courses in any of these related fields.

2020 Innovations in Intelligent Systems and Applications Conference (ASYU)

Drones in Smart-Cities: Security and Performance is the first book dedicated to drones in smart cities, helping address the many research challenges in bringing UAVs into practice. The book incorporates insights from the latest research in Internet of Things, big data, and cloud computing, 5G, and other communication technologies. It examines the design and implementation of UAV, focusing on data delivery, performability, and security. Intended for researchers, engineers, and practitioners, Drones in Smart-Cities: Security and Performance combines the technical aspects with academic theory to help implement the smart city vision around the globe. Addresses UAV and IoT for smart cities applications Examines topics as UAV safety, challenges, localization methods. QoS, simulation tools, and more Collect the relevant knowledge in one resource, saving research time and effort

2019 IEEE 2nd International Conference on Automation, Electronics and Electrical Engineering (AUTEEE)

Bring life to your robot using ROS robotic applications About This Book This book will help you boost your knowledge of ROS and give you advanced practical experience you can apply to your ROS robot platforms This is the only book that offers you step-by-step instructions to solidify your ROS understanding and gain experience using ROS tools From eminent authors, this book offers you a plethora of fun-filled examples to make your own quadcopter, turtlebot, and two-armed robots Who This Book Is For If you are a robotics developer, whether a hobbyist, researchers or professional, and are interested in learning about ROS through a hands-on approach, then this book is for you. You are encouraged to have a working knowledge of GNU/Linux systems and Python. What You Will Learn Get to know the fundamentals of ROS and apply its concepts to real robot examples Control a mobile robot to navigate autonomously in an environment Model your robot designs using URDF and Xacro, and operate them in a ROS Gazebo simulation Control a 7 degree-of-freedom robot arm for visual servoing Fly a quadcopter to autonomous waypoints Gain working knowledge of ROS tools such as Gazebo, rviz, rqt, and Move-It Control robots with mobile devices and controller boards In Detail The visionaries who created ROS developed a framework for robotics centered on the commonality of robotic systems and exploited this commonality in ROS to expedite the development of future robotic systems. From the fundamental concepts to

advanced practical experience, this book will provide you with an incremental knowledge of the ROS framework, the backbone of the robotics evolution. ROS standardizes many layers of robotics functionality from low-level device drivers to process control to message passing to software package management. This book provides step-by-step examples of mobile, armed, and flying robots, describing the ROS implementation as the basic model for other robots of these types. By controlling these robots, whether in simulation or in reality, you will use ROS to drive, move, and fly robots using ROS control. Style and approach This is an easy-to-follow guide with hands-on examples of ROS robots, both real and in simulation.

Congress on Intelligent Systems

Deep learning algorithms have brought a revolution to the computer vision community by introducing non-traditional and efficient solutions to several image-related problems that had long remained unsolved or partially addressed. This book presents a collection of eleven chapters where each individual chapter explains the deep learning principles of a specific topic, introduces reviews of up-to-date techniques, and presents research findings to the computer vision community. The book covers a broad scope of topics in deep learning concepts and applications such as accelerating the convolutional neural network inference on field-programmable gate arrays, fire detection in surveillance applications, face recognition, action and activity recognition, semantic segmentation for autonomous driving, aerial imagery registration, robot vision, tumor detection, and skin lesion segmentation as well as skin melanoma classification. The content of this book has been organized such that each chapter can be read independently from the others. The book is a valuable companion for researchers, for postgraduate and possibly senior undergraduate students who are taking an advanced course in related topics, and for those who are interested in deep learning with applications in computer vision, image processing, and pattern recognition.

Quadcopter Stabilization with Neural Network

Intelligent Autonomous Systems 12

Incorporating papers from the 12th International Symposium on Experimental Robotics (ISER), December 2010, this book examines the latest advances across the various fields of robotics. Offers insights on both theoretical concepts and experimental results.

Unmanned Aerial Systems

This text is a thorough treatment of the rapidly growing area of aerial manipulation. It details all the design steps required for the modeling and control of unmanned aerial vehicles (UAV) equipped with robotic manipulators. Starting with the physical basics of rigid-body kinematics, the book gives an in-depth presentation of local and global coordinates, together with the representation of orientation and motion in fixed- and moving-coordinate systems. Coverage of the kinematics and dynamics of unmanned aerial vehicles is developed in a succession of popular UAV configurations for multirotor systems. Such an arrangement, supported by frequent examples and end-of-chapter exercises, leads the reader from simple to more complex UAV configurations. Propulsion-system aerodynamics, essential in UAV design, is analyzed through blade-element and momentum theories, analysis which is followed by a description of drag and ground-aerodynamic effects. The central part of the book is dedicated to aerial-manipulator kinematics, dynamics, and control. Based on foundations laid in the opening chapters, this portion of the book is a structured presentation of Newton–Euler dynamic modeling that results in forward and backward equations in both fixed- and moving-coordinate systems. The Lagrange–Euler approach is applied to expand the model further, providing formalisms to model the variable moment of inertia later used to analyze the dynamics of aerial manipulators in contact with the environment. Using knowledge from sensor data, insights are presented into the ways in which linear, robust, and adaptive control techniques can be applied in aerial manipulation so as to tackle the real-world problems faced by scholars and engineers in the design and implementation of aerial robotics systems. The book is completed by path and trajectory planning with vision-based examples for tracking and manipulation.

Autonomous Control of Unmanned Aerial Vehicles

This book presents selected research papers on current developments in the fields of soft computing and signal processing from the Third International Conference on Soft Computing and Signal Processing (ICSCSP 2020). The book covers topics such as soft sets, rough sets, fuzzy logic, neural networks, genetic algorithms and machine learning and discusses various aspects of these topics, e.g., technological considerations, product implementation and application issues.

Aerial Manipulation

This book gathers papers presented during the 4th International Conference on Electrical Engineering and Control Applications. It covers new control system models, troubleshooting tips and complex system requirements, such as increased speed, precision and remote capabilities. Additionally, the papers discuss not only the engineering aspects of signal processing and various practical issues in the broad field of information transmission, but also novel technologies for communication networks and modern antenna design. This book is intended for researchers, engineers and advanced postgraduate students in the fields of control and electrical engineering, computer science and signal processing, as well as mechanical and chemical engineering.

Innovation in Wind Turbine Design

Robot Shaping

Unmanned aerial vehicles (UAVs) are being increasingly used in different applications in both military and civilian domains. These applications include surveillance, reconnaissance, remote sensing, target acquisition, border patrol, infrastructure monitoring, aerial imaging, industrial inspection, and emergency medical aid. Vehicles that can be considered autonomous must be able to make decisions and react to events without direct intervention by humans. Although some UAVs are able to perform increasingly complex autonomous manoeuvres, most UAVs are not fully autonomous; instead, they are mostly operated remotely by humans. To make UAVs fully autonomous, many technological and algorithmic developments are still required. For instance, UAVs will need to improve their sensing of obstacles and subsequent avoidance. This becomes particularly important as autonomous UAVs start to operate in civilian airspaces that are occupied by other aircraft. The aim of this volume is to bring together the work of leading researchers and practitioners in the field of unmanned aerial vehicles with a common interest in their autonomy. The contributions that are part of this volume present key challenges associated with the autonomous control of unmanned aerial vehicles, and propose solution methodologies to address such challenges, analyse the proposed methodologies, and evaluate their performance.

Autonomous Flying Robots

Photographing small objects with a quadcopter is non-trivial to perform with many common user interfaces, especially when it requires maneuvering an Unmanned Aerial Vehicle (UAV) to difficult angles in order to shoot high perspectives. The aim of this research is to employ machine learning to support better user interfaces for quadcopter photography. Human Robot Interaction (HRI) is supported by visual servoing, a specialized vision system for real-time object detection, and control policies acquired through reinforcement learning (RL). Two investigations of guided autonomy were conducted. In the first, the user directed the quadcopter with a sketch based interface, and periods of user direction were interspersed with periods of autonomous flight. In the second, the user directs the quadcopter by taking a single photo with a handheld mobile device, and the quadcopter autonomously flies to the requested vantage point. This dissertation focuses on the following problems: 1) evaluating different user interface paradigms for dynamic photography in a GPS-denied environment; 2) learning better Convolutional Neural Network (CNN) object detection models to assure a higher precision in detecting human subjects than the currently available state-of-the-art fast models; 3) transferring learning from the Gazebo simulation into the real world; 4) learning robust control policies using deep reinforcement learning to maneuver the quadcopter to multiple shooting positions with minimal human interaction.

Introduction to Autonomous Mobile Robots

The advance in robotics has boosted the application of autonomous vehicles to perform tedious and risky tasks or to be cost-effective substitutes for their - man counterparts. Based on their working environment, a rough classi cation of the autonomous vehicles would include unmanned aerial vehicles (UAVs), - manned ground vehicles (UGVs), autonomous underwater vehicles (AUVs), and autonomous surface vehicles (ASVs). UAVs, UGVs, AUVs, and ASVs are called UVs (unmanned vehicles) nowadays. In recent decades, the development of - manned autonomous vehicles have been of great interest, and different kinds of autonomous vehicles have been studied and developed all over the world. In part- ular, UAVs have many applications in emergency situations; humans often cannot come close to a dangerous natural disaster such as an earthquake, a ood, an active volcano, or a nuclear disaster. Since the development of the rst UAVs, research efforts have been focused on military applications. Recently, however, demand has arisen for UAVs such as aero-robotsand ying robotsthat can be used in emergency situations and in industrial applications. Among the wide variety of UAVs that have been developed, small-scale HUAVs (helicopter-based UAVs) have the ability to take off and land vertically as well as the ability to cruise in ight, but their most importantcapability is hovering. Hoveringat a point enables us to make more eff- tive observations of a target. Furthermore, small-scale HUAVs offer the advantages of low cost and easy operation.

Experimental Robotics IX

UAVs (Unmanned Aerial Vehicle), also known as drones, are becoming attractive in the consumer space due to their relatively low cost and their ability to operate autonomously with minimal human intervention. A user could program the drone with GPS coordinates, and the drone would comply with utmost precision. In order for the drone to operate a preprogrammed flight path, it requires a host of sensors for it to gather data and operate on that data in real time. For instance, a consumer drone typically has obstacle avoidance sensors, a GPS sensor for routing and navigation, and an IMU (Inertial Measurement Unit) for tracking position and orientation. These sensors play a crucial role in both stabilization and navigation of the drone. This report aims to investigate, analyze and understand the complexity involved in designing and implementing an autonomous quadcopter; specifically, the stabilization algorithms. In general, stabilization is achieved using some form of control algorithm. The report covers a popular approach for stabilization (PID Control) found with many open source libraries and contrasts it with an alternative machine learning approach (Neural Networks). Finally, a machine learning based algorithm is implemented and evaluated on a prototype quadcopter, and its results are presented.

From Bioinspired Systems and Biomedical Applications to Machine Learning

This book showcases new theoretical findings and techniques in the field of intelligent systems and control. It presents in-depth studies on a number of major topics, including: Multi-Agent Systems, Complex Networks, Intelligent Robots, Complex System Theory and Swarm Behavior, Event-Triggered Control and Data-Driven Control, Robust and Adaptive Control, Big Data and Brain Science, Process Control, Intelligent Sensor and Detection Technology, Deep learning and Learning Control, Guidance, Navigation and Control of Aerial Vehicles, and so on. Given its scope, the book will benefit all researchers, engineers, and graduate students who want to learn about cutting-edge advances in intelligent systems, intelligent control, and artificial intelligence.

Mobile Intelligent Autonomous Systems

Unmanned Aerial Systems: Theoretical Foundation and Applications presents some of the latest innovative approaches to drones from the point-of-view of dynamic modeling, system analysis, optimization, control, communications, 3D-mapping, search and rescue, surveillance, farmland and construction monitoring, and more. With the emergence of low-cost UAS, a vast array of research works in academia and products in the industrial sectors have evolved. The book covers the safe operation of UAS, including, but not limited to, fundamental design, mission and path planning, control theory, computer vision, artificial intelligence, applications requirements, and more. This book provides a unique reference of the state-of-the-art research and development of unmanned aerial systems, making it an essential resource for researchers, instructors and practitioners. Covers some of the most innovative approaches to drones Provides the latest state-of-the-art research and development surrounding unmanned aerial systems Presents a comprehensive reference on unmanned aerial systems, with a focus on cutting-edge technologies and recent research trends in the area

Soft Computing and Signal Processing

The theory and applications of intelligent systems is today an important field of research. This book is an up-to-date collection of seventeen chapters, written by recognized experts in the field. In an introductory mathematical foundations part an overview of generalizations of the integral inequalities for nonadditive integrals and a construction of the General Prioritized Fuzzy Satisfaction Problem is given. Then different aspects of robotics are presented, such as the differences between human beings and robots, the motion of bipedal humanoid robots, and an evaluation of different autonomous quadrotor flight controllers. Also Fuzzy Systems are presented by a model of basic planar imprecise geometric objects allowing various applications in image analysis , GIS, and robotics, as well as a type-2 fuzzy logic in a software library for developing perceptual computers, and a two--degree--of--freedom speed control solutions for a brushless Direct Current motor. The book also presents recent applications in medicine such as a Virtual Doctor System, methods for a face to face human machine interaction, and an emotion estimation, with applications for multiple diseases and the effect of the applied therapy. The last part of the book covers different applications in transportation, network monitoring, and localization of pedestrians in images.

Recent Advances in Information and Communication Technology 2015

This book constitutes the thoroughly refereed post-workshop proceedings of the First International Workshop on Modelling and Simulation for Autonomous Systems, MESAS 2014, held in Rome, Italy, in May 2014. The 32 revised full papers included in the volume were carefully reviewed and selected from 50 submissions, of which 46 were presented at the workshop. They are organized in the following topical sections: unmanned aerial vehicle, distributed simulation, robot system, military application, validation, human-machine communication, gazebo simulator, and algorithm.

Drones in Smart-Cities

The two volume set LNCS 11486 and 11487 constitutes the proceedings of the International Work-Conference on the Interplay Between Natural and Artificial Computation, IWINAC 2019, held in Almería, Spain,, in June 2019. The total of 103 contributions was carefully reviewed and selected from 190 submissions during two rounds of reviewing and improvement. The papers are organized in two volumes, one on understanding the brain function and emotions, addressing topics such as new tools for analyzing neural data, or detection emotional states, or interfacing with physical systems. The second volume deals with bioinspired systems and biomedical applications to machine learning and contains papers related bioinspired programming strategies and all the contributions oriented to the computational solutions to engineering problems in different applications domains, as biomedical systems, or big data solutions.

Lifelong Machine Learning

This second volume is a continuation of the successful first volume of this Springer book, and as well as addressing broader topics it puts a particular focus on unmanned aerial vehicles (UAVs) with Robot Operating System (ROS). Consisting of three types of chapters: tutorials, cases studies, and research papers, it provides comprehensive additional material on ROS and the aspects of developing robotics systems, algorithms, frameworks, and applications with ROS. ROS is being increasingly integrated in almost all kinds of robots and is becoming the de-facto standard for developing applications and systems for robotics. Although the research community is actively developing applications with ROS and extending its features, amount of literature references is not representative of the huge amount of work being done. The book includes 19 chapters organized into six parts: Part 1 presents the control of UAVs with ROS, while in Part 2, three chapters deal with control of mobile robots. Part 3 provides recent work toward integrating ROS with Internet, cloud and distributed systems. Part 4 offers five case studies of service robots and field experiments. Part 5 presents signal-processing tools for perception and sensing, and lastly, Part 6 introduces advanced simulation frameworks. The diversity of topics in the book makes it a unique and valuable reference resource for ROS users, researchers, learners and developers.

Experimental Robotics

Intelligent autonomous systems are emerged as a key enabler for the creation of a new paradigm of services to humankind, as seen by the recent advancement of autonomous cars licensed for driving in our streets, of unmanned aerial and underwater vehicles carrying out hazardous tasks on-site, and of space robots engaged in scientific as well as operational missions, to list only a few. This book aims at serving the researchers and practitioners in related fields with a timely dissemination of the recent progress on intelligent autonomous systems, based on a collection of papers presented at the 12th International Conference on Intelligent Autonomous Systems, held in Jeju, Korea, June 26-29, 2012. With the theme of "Intelligence and Autonomy for the Service to Humankind, the conference has covered such diverse areas as autonomous ground, aerial, and underwater vehicles, intelligent transportation systems, personal/domestic service robots, professional service robots for surgery/rehabilitation, rescue/security and space applications, and intelligent autonomous systems for manufacturing and healthcare. This volume 1 includes contributions devoted to Autonomous Ground Vehicles and Mobile Manipulators, as well as Unmanned Aerial and Underwater Vehicles and Bio-inspired Robotics.

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foreword by Lashon Booker To program an autonomous robot to act reliably in a dynamic environment is a complex task. The dynamics of the environment are unpredictable, and the robots' sensors provide noisy input. A learning autonomous robot, one that can acquire knowledge through interaction with its environment and then adapt its behavior, greatly simplifies the designer's work. A learning robot need not be given all of the details of its environment, and its sensors and actuators need not be finely tuned. Robot Shaping is about designing and building learning autonomous robots. The term "shaping" comes from experimental psychology, where it describes the incremental training of animals. The authors propose a new engineering discipline, "behavior engineering," to provide the methodologies and tools for creating autonomous robots. Their techniques are based on classifier systems, a reinforcement learning architecture originated by John Holland, to which they have added several new ideas, such as "mutespec," classifier system "energy,"and dynamic population size. In the book they present Behavior Analysis and Training (BAT) as an example of a behavior engineering methodology.

Emergent Trends in Robotics and Intelligent Systems

What is the Role of Intelligent Technologies in the Next Generation of Robots ? This monograph gives answers to this question and presents emergent trends of Intelligent Systems and Robotics. After an introductory chapter celebrating 70 year of publishing the McCulloch Pitts model the book consists of the 2 parts „Robotics" and „Intelligent Systems". The aim of the book is to contribute to shift conventional robotics in which the robots perform repetitive, pre-programmed tasks to its intelligent form, where robots possess new cognitive skills with ability to learn and adapt to changing environment. A main focus is on Intelligent Systems, which show notable achievements in solving various problems in intelligent robotics. The book presents current trends and future directions bringing together Robotics and Computational Intelligence. The contributions include widespread experimental and theoretical results on intelligent robotics such as e.g. autonomous robotics, new robotic platforms, or talking robots.

ROS Robotics By Example

This book presents a foundation for a broad class of mobile robot mapping and navigation methodologies for indoor, outdoor, and exploratory missions. It addresses the challenging problem of autonomous navigation in dynamic environments, presenting new ideas and approaches in this emerging technical domain. Coverage discusses in detail various related challenging technical aspects and addresses upcoming technologies in this field.

Robot Operating System (ROS)

Autonomous Navigation in Dynamic Environments

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Guided Autonomy for Quadcopter Photography

An updated and expanded new edition of this comprehensive guide to innovation in wind turbine design Innovation in Wind Turbine Design, Second Edition comprehensively covers the fundamentals of design, explains the reasons behind design choices, and describes the methodology for evaluating innovative systems and components. This second edition has been substantially expanded and generally updated. New content includes elementary actuator disc theory of the low induction rotor concept, much expanded discussion of offshore issues and of airborne wind energy systems, updated drive train information with basic theory of the epicyclic gears and differential drives, a clarified presentation of the basic theory of energy in the wind and fallacies about ducted rotor design related to theory, lab testing and field testing of the Katru and Wind Lens ducted rotor systems, a short review of LiDAR, latest developments of the multi-rotor concept including the Vestas 4 rotor system and a new chapter on the innovative DeepWind VAWT. The bookis divided into four main sections covering design background, technology evaluation, design themes and innovative technology examples. Key features: Expanded substantially with new content. Comprehensively covers the fundamentals of design, explains the reasons behind design choices, and describes the methodology for evaluating innovative systems and components. Includes innovative examples from working experiences for commercial clients. Updated to cover recent developments in the field. The book is a must-have reference for professional wind engineers, power engineers and turbine designers, as well as consultants, researchers and graduate students.

Digital Twin Technology

Deep Learning in Computer Vision

This carefully edited volume aims at providing readers with the most recent progress on intelligent autonomous systems, with its particular emphasis on intelligent autonomous ground, aerial and underwater vehicles as well as service robots for home and healthcare under the context of the aforementioned convergence. "Frontiers of Intelligent Autonomous Systems" includes thoroughly revised and extended papers selected from the 12th International Conference on Intelligent Autonomous Systems (IAS-12), held in Jeju, Korea, June 26-29, 2012. The editors chose 35 papers out of the 202 papers presented at IAS-12 which are organized into three chapters: Chapter 1 is dedicated to autonomous navigation and mobile manipulation, Chapter 2 to unmanned aerial and underwater vehicles and Chapter 3 to service robots for home and healthcare. To help the readers to easily access this volume, each chapter starts with a chapter summary introduced by one of the editors: Chapter 1 by Sukhan Lee, Chapter 2 by Kwang Joon Yoon and Chapter 3 by Jangmyung Lee.

Pattern Recognition

This book constitutes the proceedings of the 12th Mexican Conference on Pattern Recognition, MCPR 2020, which was due to be held in Morelia, Mexico, in June 2020. The conference was held virtually due to the COVID-19 pandemic. The 31 papers presented in this volume were carefully reviewed and selected from 67 submissions. They were organized in the following topical sections: pattern recognition techniques; image processing and analysis; computer vision; industrial and medical applications of pattern recognition; natural language processing and recognition; artificial intelligence techniques and recognition.

Sliding Mode Control in Electro-Mechanical Systems

The International Symposium on Experimental Robotics (ISER) is a series of bi-annual meetings which are organized in a rotating fashion around North America, Europe and Asia/Oceania. The goal of ISER is to provide a forum for research in robotics that focuses on novelty of theoretical contributions validated by experimental results. The meetings are conceived to bring together, in a small group setting, researchers from around the world who are in the forefront of experimental robotics research. This unique reference presents the latest advances across the various fields of robotics, with ideas that are not only conceived conceptually but also verified experimentally. It collects contributions on the current developments and new directions in the field of experimental robotics, which are based on the papers presented at the Ninth ISER held in Singapore.

Deep Learning

Provides an overview of general deep learning methodology and its applications to a variety of signal and information processing tasks

Proceedings of 2019 Chinese Intelligent Systems Conference

Most of the business sectors consider the Digital Twin concept as the next big thing in the industry. A current state analysis of their digital counterparts helps in the prediction of the future of physical assets. Organizations obtain better insights on their product performance through the implementation of Digital Twins, and the applications of the technology are frequently in sectors such as manufacturing, automobile, retail, health care, smart cities, industrial IoT, etc. This book explores the latest developments and covers the significant challenges, issues, and advances in Digital Twin Technology. It will be an essential resource for anybody involved in related industries, as well as anybody interested in learning more about this nascent technology. This book includes: The future, present, and past of Digital Twin Technology. Digital twin technologies across the Internet of Drones, which developed various perceptive and autonomous capabilities, towards different control strategies such as object detection, navigation, security, collision avoidance, and backup. These approaches help to deal with the expansive growth of big data solutions. The recent digital twin concept in agriculture, which offers the vertical framing by IoT installation development to enhance the problematic food supply situation. It also allows for significant energy savings practices. It is highly required to overcome those challenges in developing advanced imaging methods of disease detection & prediction to achieve more accuracy in large land areas of crops. The welfare of upcoming archetypes such as digitalization in forensic analysis. The ideas of digital twin have arisen to style the corporeal entity and associated facts reachable software and customers over digital platforms. Wind catchers as earth building: Digital Twins vs. green sustainable architecture.

Frontiers of Intelligent Autonomous Systems

From an engineering standpoint, the increasing complexity of robotic systems and the increasing demand for more autonomously learning robots, has become essential. This book is largely based on the successful workshop "From motor to interaction learning in robots" held at the IEEE/RSJ International Conference on Intelligent Robot Systems. The major aim of the book is to give students interested the topics described above a chance to get started faster and researchers a helpful compandium.

Proceedings of the 4th International Conference on Electrical Engineering and Control Applications

This book presents recent research work and results in the area of communication and information technologies. The book includes the main results of the 11th International Conference on Computing and Information Technology (IC2IT) held during July 2nd-3rd, 2015 in Bangkok, Thailand. The book is divided into the two main parts Data Mining and Machine Learning as well as Data Network and Communications. New algorithms and methods of data mining asr discussed as well as innovative applications and state-of-the-art technologies on data mining, machine learning and data networking.