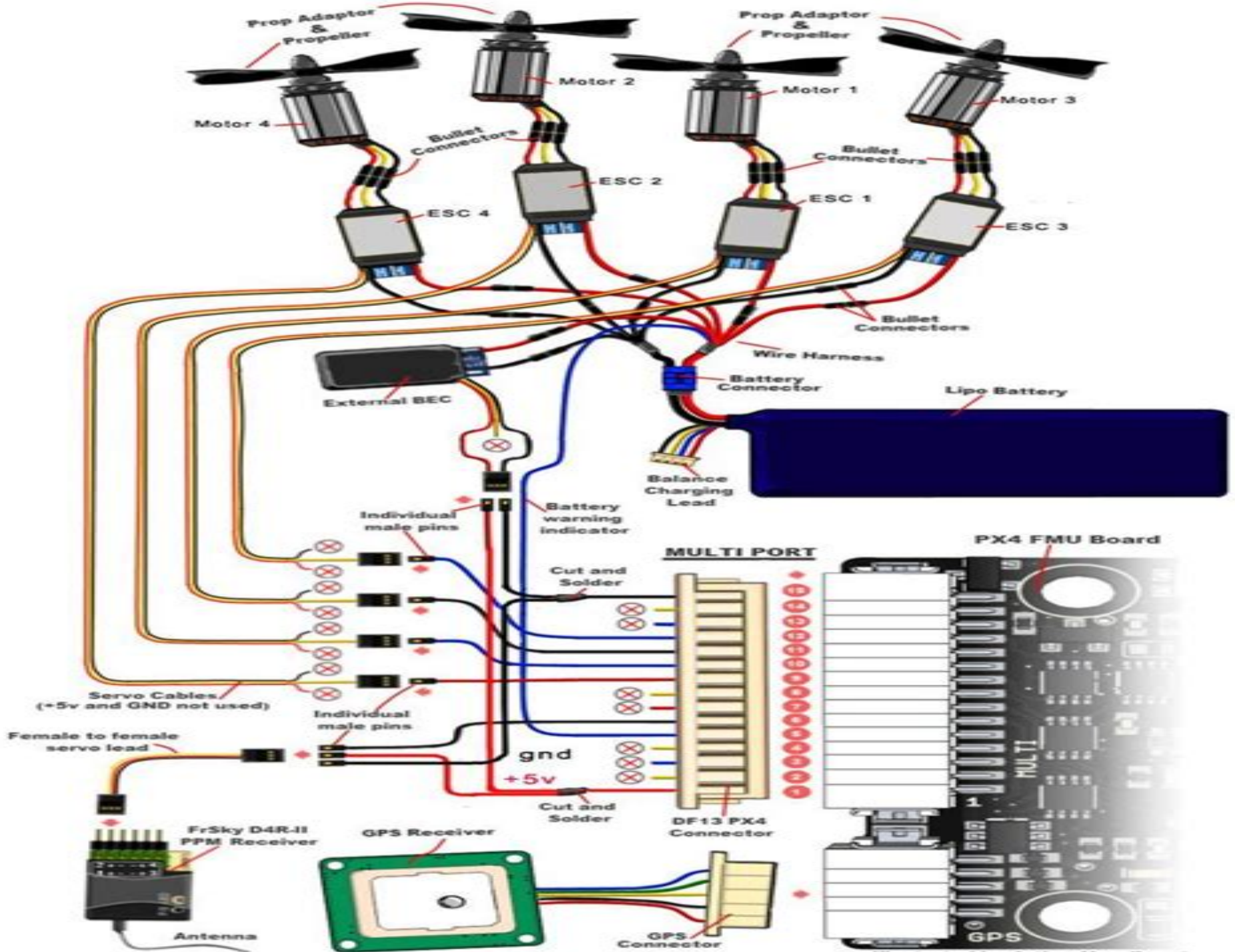




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Service Robotics and Mechatronics Keiichi Shirase, Seiji Aoyagi, 2009-10-24 In a world suffering from an ageing population and declining birth rate service robotics and mechatronics have an increasingly vital role to play in maintaining a safe and sustainable environment for everyone Mechatronics can be used in the reconstruction or restoration of various environments which we rely upon to survive for example the reconstruction of a city after an earthquake or the restoration of polluted waters This collection of papers was originally presented at the 7th International Conference on Machine Automation 2008 in Awaji Japan and covers a variety of new trends in service robotics and mechatronics Service Robotics and Mechatronics showcases the latest research in the area to provide researchers and scientists with an up to date source of knowledge and basis for further study as well as offering graduate students valuable reference material

Servomechanisms: Bulletin of Automatic and Manual Control Abstracts ,1966 **Design of a Four-rotor Autonomous Helicopter for Vehicle-based Phased Antenna Arrays** Sean Hugh Breheny, 2008 **Scientific and Technical Aerospace Reports** ,1972 Lists citations with abstracts for aerospace related reports obtained from world wide sources and announces documents that have recently been entered into the NASA Scientific and Technical Information Database *NASA Tech Briefs* ,1988 *Selected papers from the 2nd International Symposium on UAVs, Reno, U.S.A. June 8-10, 2009* Kimon P. Valavanis, Randal Beard, Paul Oh, Anibal Ollero, Leslie A. Piegl, Hayong Shin, 2011-04-11 In the last decade significant changes have occurred in the field of vehicle motion planning and for UAVs in particular UAV motion planning is especially difficult due to several complexities not considered by earlier planning strategies the increased 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 difficult 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 field 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 **NASA Patent Abstracts Bibliography** United States. National Aeronautics and Space Administration. Scientific and Technical Information

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