Grid Finder

Niko Sünderhauf

Progress in Artificial Intelligence Luis Miguel Correia,Luís Paulo Reis,José Manuel Cascalho,2013-09-04 This book constitutes the refereed proceedings of the 16th Portuguese Conference on Artificial Intelligence, EPIA 2013, held in Angra do Heroísmo, Azores, Portugal, in September 2013. The 45 revised full papers presented were carefully reviewed and selected from a total of 157 submissions. The papers are organized in the following topical sections: ambient intelligence and affective environments; artificial intelligence in transportation systems; artificial life and evolutionary algorithms; computational methods in bioinformatics and systems biology; general artificial intelligence; intelligent robotics; knowledge discovery and business intelligence; multi-agent systems: theory and applications; social simulation and modeling; and text mining and applications.

FCS Sustainable Tourism in SA L2 Clive Duncan,2008

Intelligent Robotics and Applications YongAn Huang,Hao Wu,Honghai Liu,Zhouping Yin,2017-08-04 The three volume set LNAI 10462, LNAI 10463, and LNAI 10464 constitutes the refereed proceedings of the 10th International Conference on Intelligent Robotics and Applications, ICIRA 2017, held in Wuhan, China, in August 2017. The 235 papers presented in the three volumes were carefully reviewed and selected from 310 submissions. The papers in this third volume of the set are organized in topical sections on sensors and actuators; mobile robotics and path planning;

virtual reality and artificial intelligence; aerial and space robotics; mechatronics and intelligent manufacturing.

   A DSmT-based Fusion Machine for Robot's Map Reconstruction Xinhan Huang,Xinde Li,Min Wang, Characteristics of uncertainty and imprecision, even imperfection is presented from knowledge acquisition in map reconstruction of autonomous mobile robots. Especially in the course of building grid map using sonar, this characteristic of uncertainty is especially servere.

   Human Behavior Understanding in Networked Sensing Paolo Spagnolo,Pier Luigi Mazzeo,Cosimo Distante,2014-11-06 This book provides a broad overview of both the technical challenges in sensor network development, and the real-world applications of distributed sensing. Important aspects of distributed computing in large-scale networked sensor systems are analyzed in the context of human behavior understanding, including topics on systems design tools and techniques. Additionally, the book examines a varied range of applications. Features: contains valuable contributions from an international selection of leading experts in the field; presents a high-level introduction to the aims and motivations underpinning distributed sensing; describes decision-making algorithms in the presence of complex sensor networks; provides a detailed analysis of the design, implementation, and development of a distributed network of homogeneous or heterogeneous sensors; reviews the application of distributed sensing to human behavior understanding and autonomous intelligent

vehicles; includes a helpful glossary and a list of acronyms.

  Mac OS X Power Hound Rob Griffiths,2004 As it turns out, Mac OS X Panther harbors just as many delicious secrets as any system that came before--users just have to know where to find them. Inside, readers will find 560 high-octane secrets in every conceivable category, including The Desktop and Finder, iApps, Mac OS X Programs, Mastering the System, and Terminal.

  Robot Localization and Map Building Hanafiah Yussof,2010-03-01 Localization and mapping are the essence of successful navigation in mobile platform technology. Localization is a fundamental task in order to achieve high levels of autonomy in robot navigation and robustness in vehicle positioning. Robot localization and mapping is commonly related to cartography, combining science, technique and computation to build a trajectory map that reality can be modelled in ways that communicate spatial information effectively. This book describes comprehensive introduction, theories and applications related to localization, positioning and map building in mobile robot and autonomous vehicle platforms. It is organized in twenty seven chapters. Each chapter is rich with different degrees of details and approaches, supported by unique and actual resources that make it possible for readers to explore and learn the up to date knowledge in robot navigation technology. Understanding the theory and principles described in this book requires a multidisciplinary background of robotics, nonlinear system, sensor network,

network engineering, computer science, physics, etc.

Using Robots in Hazardous Environments Y Baudoin,M K Habib,2010-12-20 There have been major recent advances in robotic systems that can replace humans in undertaking hazardous activities in demanding or dangerous environments. Published in association with the CLAWAR (Climbing and Walking Robots and Associated Technologies Association) (www.clawar.org), this important book reviews the development of robotic systems for de-mining and other risky activities such as fire-fighting. Part one provides an overview of the use of robots for humanitarian de-mining work. Part two discusses the development of sensors for mine detection whilst Part thee reviews developments in both teleoperated and autonomous robots. Building on the latter, Part four concentrates on robot autonomous navigation. The final part of the book reviews research on multi-agent-systems (MAS) and the multi-robotics-systems (MRS), promising tools that take into account modular design of mobile robots and the use of several robots in multi-task missions. With its distinguished editors and international team of contributors, Using robots in hazardous environments: landmine detection, de-mining and other applications is a standard reference for all those researching the use of robots in hazardous environments as well as government and other agencies wishing to use robots for dangerous tasks such as landmine detection and disposal. Reviews the development of robotic systems for de-mining and other risky activities Discusses the development and

applications of sensors for mine detection using different robotic systems Examines research on multi-agent-systems and multi-robotics systems

Robot 2015: Second Iberian Robotics Conference
Luís Paulo Reis,António Paulo Moreira,Pedro U. Lima,Luis Montano,Victor Muñoz-Martinez,2015-12-01 This book contains a selection of papers accepted for presentation and discussion at ROBOT 2015: Second Iberian Robotics Conference, held in Lisbon, Portugal, November 19th-21th, 2015. ROBOT 2015 is part of a series of conferences that are a joint organization of SPR – "Sociedade Portuguesa de Robótica/ Portuguese Society for Robotics", SEIDROB – Sociedad Española para la Investigación y Desarrollo de la Robótica/ Spanish Society for Research and Development in Robotics and CEA-GTRob – Grupo Temático de Robótica/ Robotics Thematic Group. The conference organization had also the collaboration of several universities and research institutes, including: University of Minho, University of Porto, University of Lisbon, Polytechnic Institute of Porto, University of Aveiro, University of Zaragoza, University of Malaga, LIACC, INESC-TEC and LARSyS. Robot 2015 was focussed on the Robotics scientific and technological activities in the Iberian Peninsula, although open to research and delegates from other countries. The conference featured 19 special sessions, plus a main/general robotics track. The special sessions were about: Agricultural Robotics and Field Automation; Autonomous Driving and Driver Assistance Systems; Communication Aware Robotics; Environmental Robotics; Social Robotics: Intelligent and Adaptable AAL Systems; Future

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Industrial Robotics Systems; Legged Locomotion Robots; Rehabilitation and Assistive Robotics; Robotic Applications in Art and Architecture; Surgical Robotics; Urban Robotics; Visual Perception for Autonomous Robots; Machine Learning in Robotics; Simulation and Competitions in Robotics; Educational Robotics; Visual Maps in Robotics; Control and Planning in Aerial Robotics, the XVI edition of the Workshop on Physical Agents and a Special Session on Technological Transfer and Innovation.

Neural Information Processing Akira Hirose,Seiichi Ozawa,Kenji Doya,Kazushi Ikeda,Minho Lee,Derong Liu,2016-09-30 The four volume set LNCS 9947, LNCS 9948, LNCS 9949, and LNCS 9950 constitutes the proceedings of the 23rd International Conference on Neural Information Processing, ICONIP 2016, held in Kyoto, Japan, in October 2016. The 296 full papers presented were carefully reviewed and selected from 431 submissions. The 4 volumes are organized in topical sections on deep and reinforcement learning; big data analysis; neural data analysis; robotics and control; bio-inspired/energy efficient information processing; whole brain architecture; neurodynamics; bioinformatics; biomedical engineering; data mining and cybersecurity workshop; machine learning; neuromorphic hardware; sensory perception; pattern recognition; social networks; brain-machine interface; computer vision; time series analysis; data-driven approach for extracting latent features; topological and graph based clustering methods; computational intelligence; data mining;

deep neural networks; computational and cognitive neurosciences; theory and algorithms.

Autonomous Land Vehicles Karsten Berns,Ewald Puttkamer,2010-02-23 The economic potential of autonomous mobile robots will increase tremendously during the next years. Service robots such as cleaning machines and inspection or assistance robots will bring us great support in our daily lives. This textbook provides an introduction to the methods of controlling these robotic systems. Starting from mobile robot kinematics, the reader receives a systematic overview of the basic problems as well as methods and algorithms used for solving them. Localisation, object recognition, map building, navigation and control architectures for autonomous vehicles will be discussed in detail. In conclusion, a survey of specific service robot applications is included as well. This book is a very useful introduction to mobile robotics for beginners as well as advanced students and engineers.

Intelligent Interactive Multimedia Systems and Services 2017 Giuseppe De Pietro,Luigi Gallo,Robert J. Howlett,Lakhmi C. Jain,2017-05-26 This book constitutes the refereed proceedings of the Tenth International KES Conference on Intelligent Interactive Multimedia Systems and Services: IIMSS-17. It includes 57 full papers organized into topical sections, ranging from visual data processing to big data analytics, and from multimedia to intelligent and cognitive systems. The conference took place as part of the Smart Digital Futures 2017 multi-theme conference,

held in Vilamoura, Algarve, Portugal on 21—23 June 2017, which brings together AMSTA, IDT, InHorizons, InMed, SEEL and IIMSS in one venue. It provided an international forum for researchers and scientists to share their work and experiences in the field of multimedia and intelligent interactive systems and services.

   <u>Air Force AFM.</u> ,1959

   <u>USAF Communications-electronics Doctrine, Short Title: CED 3900</u> United States. Department of the Air Force,1959

   Foundations of Robotics Damith Herath,David St-Onge,2022-09-25 This open access book introduces key concepts in robotics in an easy to understand language using an engaging project-based approach. It covers contemporary topics in robotics, providing an accessible entry point to fundamentals in all the major domains. A section is dedicated to introducing programming concepts using Python, which has become a language of choice in robotics and AI. The book also introduces the reader to the Robot Operating System (ROS), the ubiquitous software and algorithmic framework used by researchers and the industry. The book provides an inspired, up-to-date and multidisciplinary introduction to robotics in its many forms, including emerging topics related to robotics on Machine Learning, ethics, Human-Robot Interaction, and Design Thinking. The book also includes interviews with industry experts, providing an additional layer of insight into the world of robotics. The book is made open access through the generous support from Kinova Robotics. The book is suitable as an

undergraduate textbook in a relevant engineering course. It is also suitable for students in art and design, high school students, and self-learners who would like to explore foundational concepts in robotics. "This book provides the 'foundation' for understanding how robots work. It is the accessible introduction that artists and engineers have been waiting for." - Ken Goldberg, William S. Floyd Jr. Distinguished Chair in Engineering, UC Berkeley.

   Switchable Constraints for Robust Simultaneous Localization and Mapping and Satellite-Based Localization Niko Sünderhauf,2023-04-07 Simultaneous Localization and Mapping (SLAM) has been a long-standing research problem in robotics. It describes the problem of a robot mapping an unknown environment, while simultaneously localizing in it with the help of the incomplete map. This book describes a technique called Switchable Constraints.Switchable Constraints help to increase the robustness of SLAM against data association errors and in particular against false positive loop closure detections. Such false positive loop closure detections can occur when the robot erroneously assumes it re-observed a landmark it has already mapped or when the appearance of the observed surroundings is very similar to the appearance of other places in the map. Ambiguous observations and appearances are very common in human-made environments such as office floors or suburban streets, making robustness against spurious observations a key challenge in SLAM. The book summarizes the foundations of factor graph-based SLAM techniques.

It explains the problem of data association errors before introducing the novel idea of Switchable Constraints. We present a mathematical derivation and probabilistic interpretation of Switchable Constraints along with evaluations on different datasets. The book shows that Switchable Constraints are applicable beyond SLAM problems and demonstrates the efficacy of this technique to improve the quality of satellite-based localization in urban environments, where multipath and non-line-of-sight situations are common error sources.

   Robot Intelligence Technology and Applications 2 Jong-Hwan Kim,Eric T . Matson,Hyun Myung,Peter Xu,Fakhri Karray,2014-03-21 We are facing a new technological challenge on how to store and retrieve knowledge and manipulate intelligence for autonomous services by intelligent systems which should be capable of carrying out real world tasks autonomously. To address this issue, robot researchers have been developing intelligence technology (InT) for "robots that think" which is in the focus of this book. The book covers all aspects of intelligence from perception at sensor level and reasoning at cognitive level to behavior planning at execution level for each low level segment of the machine. It also presents the technologies for cognitive reasoning, social interaction with humans, behavior generation, ability to cooperate with other robots, ambience awareness and an artificial genome that can be passed on to other robots. These technologies are to materialize cognitive intelligence, social intelligence, behavioral intelligence, collective

intelligence, ambient intelligence and genetic intelligence. The book aims at serving researchers and practitioners with a timely dissemination of the recent progress on robot intelligence technology and its applications, based on a collection of papers presented at the at the 2nd International Conference on Robot Intelligence Technology and Applications (RiTA), held in Denver, USA, December 18-20, 2013.

Peak District Treasure Hunts Ian Almond,2004

DK Eyewitness Travel Guide Chicago DK Eyewitness,2017-01-17 DK Eyewitness Travel Guide: Chicago will lead you through the best attractions the city has to offer, including fully illustrated coverage of all the major sights from Lincoln Park Zoo to the Art Institute of Chicago. The fully updated guide includes unique illustrated cutaways, floor plans, and reconstructions of the city's architecture, plus a pull-out city map clearly marked with attractions from the guidebook and an easy-to-use street index. DK Eyewitness Travel Guide: Chicago provides all the insider tips you need, whether you're shopping on Michigan Avenue, enjoying the rides at the Navy Pier funfair, taking in the view from the Sears Tower, or exploring the areas outside the city. Detailed listings will guide you to hotels, restaurants, bars, nightlife, and shopping for all budgets. Street maps to guide you through the city, with reliable information on getting around. With hundreds of full-color photographs, hand-drawn illustrations, and custom maps that brighten every page, DK Eyewitness Travel Guide: Chicago truly shows you this city as no one else can.

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