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Embedded Robotics Helicopter Projects Guide

R Sandford



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Robots, Drones, UAVs and UGVs for Operation and Maintenance Diego Galar, Uday Kumar, Dammika

Seneviratne, 2020-05-07 Industrial assets such as railway lines roads pipelines are usually huge span long distances and can be divided into clusters or segments that provide different levels of functionality subject to different loads degradations and environmental conditions and their efficient management is necessary The aim of the book is to give comprehensive understanding about the use of autonomous vehicles context of robotics for the utilization of inspection and maintenance activities in industrial asset management in different accessibility and hazard levels The usability of deploying inspection vehicles in an autonomous manner is explained with the emphasis on integrating the total process Key Features Aims for solutions for maintenance and inspection problems provided by robotics drones unmanned air vehicles and unmanned ground vehicles Discusses integration of autonomous vehicles for inspection and maintenance of industrial assets Covers the industrial approach to inspection needs and presents what is needed from the infrastructure end Presents the requirements for robot designers to design an autonomous inspection and maintenance system Includes practical case studies from industries

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 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

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