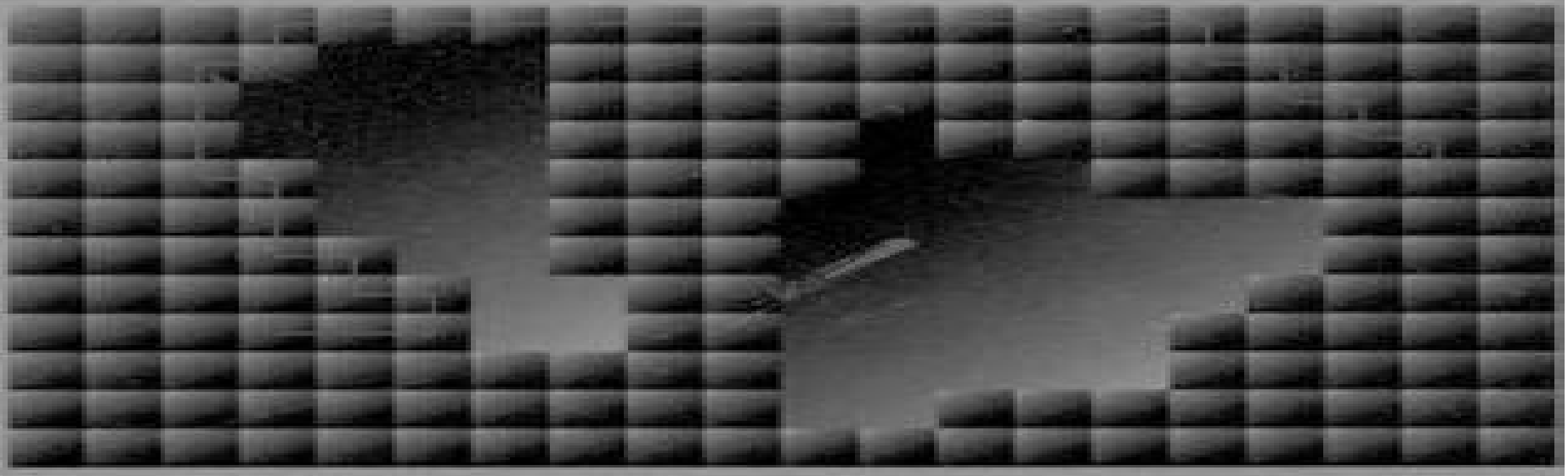
World Scientific Series in Robotics and Intelligent Systems — Vol. 20

OBSTACLE AVOIDANCE IN MULTI-ROBOT SYSTEMS

Experiments in Parallel Genetic Algorithms



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Obstacle Avoidance In Multirobot Systems Experiments In Parallel Genetic Algorithms

Oluwole O. Taiwo

Obstacle Avoidance In Multirobot Systems Experiments In Parallel Genetic Algorithms:

Obstacle Avoidance in Multi-robot Systems Mark A. C. Gill,Albert Y. Zomaya,1998 Obstacle Avoidance in Multi robot Systems Experiments in Parallel Genetic Algorithms offers a novel framework for solving the path planning problem for robot manipulators Simple and efficient solutions are proposed for the path planning problem based on genetic algorithms One of the attractive features of genetic algorithms is their ability to solve formidable problems in a robust and straightforward manner Moreover genetic algorithms are inherently parallel in nature which makes them ideal candidates for parallel computing implementations By combining the robustness of genetic algorithms with the power of parallel computers this book provides an effective and practical approach to solving path planning problems The book gives details of implementations that allow a better understanding of the complexities involved in the development of parallel path planning algorithms The material presented is interdisciplinary in nature it combines topics from robotics genetic algorithms and parallel processing The book can be used by practitioners and researchers in computer science and engineering

Interdisciplinary Approaches To Robot Learning Andreas Birk,Yiannis Demiris,2000-06-12 Robots are being used in increasingly complicated and demanding tasks often in environments that are complex or even hostile Underwater space and volcano exploration are just some of the activities that robots are taking part in mainly because the environments that are being explored are dangerous for humans Robots can also inhabit dynamic environments for example to operate among humans not just in factories but also taking on more active roles Recently for instance they have made their way into the home entertainment market Given the variety of situations that robots will be placed in learning becomes increasingly important Robot learning is essentially about equipping robots with the capacity to improve their behaviour over time based on their incoming experiences The papers in this volume present a variety of techniques Each paper provides a mini introduction to a subfield of robot learning Some also give a fine introduction to the field of robot learning as a whole There is one unifying aspect to the work reported in the book namely its interdisciplinary nature especially in the combination of robotics computer science and biology This approach has two important benefits first the study of learning in biological systems can provide robot learning scientists and engineers with valuable insights into learning mechanisms of proven functionality and versatility second computational models of learning in biological systems and their implementation in simulated agents and robots can provide researchers of biological systems with a powerful platform for the development and testing of learning theories **Adaptive Neural Network Control Of Robotic Manipulators** Sam Shuzhi Ge,Christopher J Harris,Tong Heng Lee,1998-12-04 Recently there has been considerable research interest in neural network control of robots and satisfactory results have been obtained in solving some of the special issues associated with the problems of robot control in an on and off fashion This book is dedicated to issues on adaptive control of robots based on neural networks The text has been carefully tailored to i give a comprehensive study of robot dynamics ii present structured network models for

robots and iii provide systematic approaches for neural network based adaptive controller design for rigid robots flexible joint robots and robots in constraint motion Rigorous proof of the stability properties of adaptive neural network controllers is provided Simulation examples are also presented to verify the effectiveness of the controllers and practical implementation issues associated with the controllers are also discussed **High-level Feedback Control With Neural Networks** Young Ho Kim,Frank L Lewis,1998-09-28 Complex industrial or robotic systems with uncertainty and disturbances are difficult to control As system uncertainty or performance requirements increase it becomes necessary to augment traditional feedback controllers with additional feedback loops that effectively add intelligence to the system Some theories of artificial intelligence AI are now showing how complex machine systems should mimic human cognitive and biological processes to improve their capabilities for dealing with uncertainty This book bridges the gap between feedback control and AI It provides design techniques for high level neural network feedback control topologies that contain servo level feedback control loops as well as AI decision and training at the higher levels Several advanced feedback topologies containing neural networks are presented including dynamic output feedback reinforcement learning and optimal design as well as a fuzzy logic reinforcement controller The control topologies are intuitive yet are derived using sound mathematical principles where proofs of stability are given so that closed loop performance can be relied upon in using these control systems Computer simulation examples are given to illustrate the performance **Odour Detection by Mobile Robots** R. Andrew Russell,1999 Insects are extremely successful creatures thriving in our ever changing Odour Sensing Technology Odour Discrimination Airflow Broadcast Chemical Signals Chemical Markings as Signals Trail Following Coding Information into Trails Heat as a Short Lived Marker Readership Graduate students researchers in robotics mechatronics artificial intelligence **Fuzzy Logic Control** H. B. Verbruggen,Robert Babu?ka,1999 Fuzzy logic control has become an important methodology in control engineering This volume deals with applications of fuzzy logic control in various domains The contributions are divided into three parts The first part consists of two state of the art tutorials on fuzzy control and fuzzy modeling Surveys of advanced methodologies are included in the second part These surveys address fuzzy decision making and control fault detection isolation and diagnosis complexity reduction in fuzzy systems and neuro fuzzy methods The third part contains application oriented contributions from various fields such as process industry cement and ceramics vehicle control and traffic management electromechanical and production systems avionics biotechnology and medical applications The book is intended for researchers both from the academic world and from industry *Sensor Modelling, Design And Data Processing For Autonomous Navigation* Martin David Adams,1999-02-04 This invaluable book presents an unbiased framework for modelling and using sensors to aid mobile robot navigation It addresses the problem of accurate and reliable sensing in confined environments and makes a detailed analysis of the design and construction of a low cost optical range finder This is followed by a quantitative model for determining the sources and propagation of noise within the sensor The

physics behind the causes of erroneous data is also used to derive a model for detecting and labelling such data as false In addition the author s data processing algorithms are applied to the problem of environmental feature extraction This forms the basis of a solution to the problem of mobile robot localisation The book develops a relationship between the kinematics of a mobile robot during the execution of successive manoeuvres and the sensed features Results which update a mobile vehicle s position using features from 2D and 3D scans are presented *American Book Publishing Record* ,1998 **Forthcoming Books** Rose Arny,1998-06 *Computer & Control Abstracts* ,1996 **International Aerospace Abstracts** ,1993

Intelligent Robotics and Applications Haibin Yu,Jinguo Liu,Lianqing Liu,Zhaojie Ju,Yuwang Liu,Dalin Zhou,2019-08-05 The volume set LNAI 11740 until LNAI 11745 constitutes the proceedings of the 12th International Conference on Intelligent Robotics and Applications ICIRA 2019 held in Shenyang China in August 2019 The total of 378 full and 25 short papers presented in these proceedings was carefully reviewed and selected from 522 submissions The papers are organized in topical sections as follows Part I collective and social robots human biomechanics and human centered robotics robotics for cell manipulation and characterization field robots compliant mechanisms robotic grasping and manipulation with incomplete information and strong disturbance human centered robotics development of high performance joint drive for robots modular robots and other mechatronic systems compliant manipulation learning and control for lightweight robot Part II power assisted system and control bio inspired wall climbing robot underwater acoustic and optical signal processing for environmental cognition piezoelectric actuators and micro nano manipulations robot vision and scene understanding visual and motional learning in robotics signal processing and underwater bionic robots soft locomotion robot teleoperation robot autonomous control of unmanned aircraft systems Part III marine bio inspired robotics and soft robotics materials mechanisms modelling and control robot intelligence technologies and system integration continuum mechanisms and robots unmanned underwater vehicles intelligent robots for environment detection or fine manipulation parallel robotics human robot collaboration swarm intelligence and multi robot cooperation adaptive and learning control system wearable and assistive devices and robots for healthcare nonlinear systems and control Part IV swarm intelligence unmanned system computational intelligence inspired robot navigation and SLAM fuzzy modelling for automation control and robotics development of ultra thin film flexible sensors and tactile sensation robotic technology for deep space exploration wearable sensing based limb motor function rehabilitation pattern recognition and machine learning navigation localization Part V robot legged locomotion advanced measurement and machine vision system man machine interactions fault detection testing and diagnosis estimation and identification mobile robots and intelligent autonomous systems robotic vision recognition and reconstruction robot mechanism and design Part VI robot motion analysis and planning robot design development and control medical robot robot intelligence learning and linguistics motion control computer integrated manufacturing robot cooperation virtual and augmented reality education in mechatronics engineering robotic drilling and sampling technology

automotive systems mechatronics in energy systems human robot interaction **Robot Colonies** Ronald C. Arkin,George A. Bekey,2013-03-14 Robots in groups or colonies can exhibit an enormous variety and richness of behaviors which cannot be observed with singly autonomous systems Of course this is analogous to the amazing variety of group animal behaviors which can be observed in nature In recent years more and more investigators have started to study these behaviors The studies range from classifications and taxonomies of behaviors to development of architectures which cause such group activities as flocking or swarming and from emphasis on the role of intelligent agents in such groups to studies of learning and obstacle avoidance There used to be a time when many robotics researchers would question those who were interested in working with teams of robots Why are you worried about robotic teams when it s hard enough to just get one to work This issue responds to that question Robot Colonies provides a new approach to task problem solving that is similar in many ways to distributed computing Multiagent robotic teams offer the possibility of spatially distributed parallel and concurrent perception and action A paradigm shift results when using multiple robots providing a different perspective on how to carry out complex tasks New issues such as interagent communications spatial task distribution heterogeneous or homogeneous societies and interference management are now central to achieving coordinated and productive activity within a colony Fortunately mobile robot hardware has evolved sufficiently in terms of both cost and robustness to enable these issues to be studied on actual robots and not merely in simulation Robot Colonies presents a sampling of the research in this field While capturing a reasonable representation of the most important work within this area its objective is not to be a comprehensive survey but rather to stimulate new research by exposing readers to the principles of robot group behaviors architectures and theories Robot Colonies is an edited volume of peer reviewed original research comprising eight invited contributions by leading researchers This research work has also been published as a special issue of Autonomous Robots Volume 4 Number 1

Formation and Obstacle Avoidance in the Unknown Environment of Multi-Robot System Tao Zhang,2011 Formation and Obstacle Avoidance in the Unknown Environment of Multi Robot System Optimal Planning of Robot Calibration Experiments by Genetic Algorithms Weizhen Huang,1995 *Safe and Shorter Path Planning for Autonomous Mobile Robots by Multi-objective Island-based Parallel Genetic Algorithm with Dominating Pool* Yau-Zen Chang,2018

Formation and Obstacle Avoidance in the Unknown Environment of Multi-Robot System Tao Zhang,Jingyan Song,Song Chen,Xiaqin Li,Yi Zhu,Yu Cheng,2011 **Multiple Path-planning for Group of Mobile Robots Using Genetic Algorithms** Oluwole O. Taiwo,2003 **Bericht** ,1981 *Comparison of Obstacle Avoidance Algorithms for a Multi-link Robot by Computer Simulations* Hoo Dennis Ong,1987

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