

**Aníbal Ollero
Iván Maza (Eds.)**

Multiple Heterogeneous Unmanned Aerial Vehicles

Multiple Heterogeneous Unmanned Aerial Vehicles Springer Tracts In Advanced Robotics

Aníbal Ollero, Iván Maza



Multiple Heterogeneous Unmanned Aerial Vehicles Springer Tracts In Advanced Robotics:

Multiple Heterogeneous Unmanned Aerial Vehicles Aníbal Ollero, Iván Maza, 2007-10-25 Aerial robots can be considered as an evolution of the Unmanned Aerial Vehicles UAVs This book provides a quite complete overview of issues related to aerial robotics addressing problems ranging from flight control to terrain perception and mission planning and execution The major challenges and potentials of heterogeneous UAVs are comprehensively explored It builds on the results of the European project COMETS and highlights a number of key research topics in the area of UAV development including communication perception teleoperation and decision making The monograph emphasizes the current state of technology the existing problems and potentialities of systems consisting of multiple UAVs which are heterogeneous in view of the different characteristics of the aerial vehicles the different on board payloads and the different on board information processing capabilities The book also examines potential applications of UAVs and details a relevant application case forest fire detection and monitoring

Unmanned Aircraft Systems Kimon P. Valavanis, Paul Oh, Les A. Piegl, 2008-12-21 Unmanned Aircraft Systems UAS have seen unprecedented levels of growth during the last decade in both military and civilian domains It is anticipated that civilian applications will be dominant in the future although there are still barriers to be overcome and technical challenges to be met Integrating UAS into for example civilian space navigation autonomy see detect and avoid systems smart designs system integration vision based navigation and training to name but a few areas will be of prime importance in the near future This special volume is the outcome of research presented at the International Symposium on Unmanned Aerial Vehicles held in Orlando Florida USA from June 23 25 2008 and presents state of the art findings on topics such as UAS operations and integration into the national airspace system UAS navigation and control micro mini small UAVs UAS simulation testbeds and frameworks UAS research platforms and applications UAS applications This book aims at serving as a guide tool on UAS for engineers and practitioners academics government agencies and industry Previously published in the Journal of Intelligent and Robotic Systems 54 1 3 2009 [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

Geolocation of RF Signals Ilir Progri, 2011-01-15 Geolocation of RF Signals Principles and Simulations offers an overview of the best practices and innovative techniques in the art and science of geolocation over the last twenty years It covers all research and development aspects including theoretical analysis RF signals geolocation techniques key block diagrams and practical principle simulation examples in the frequency band from 100 MHz to 18 GHz or even 60 GHz Starting with RF signals the book progressively examines various signal bands such as VLF LF MF HF VHF UHF L S C X Ku and K and the corresponding geolocation requirements per band and per application to achieve required performance objectives of up to 0.0 precision Part II follows a step by step approach of RF geolocation techniques and concludes with notes on state of the art geolocation designs as well as advanced features found in signal generator instruments Drawing upon years of practical experience and using numerous examples and illustrative applications Ilir Progri provides a comprehensive introduction to Geolocation of RF Signals and includes hands on real world labs and applications using MATLAB in the areas of RF signals specifications RF geolocation distributed wireless communications networks and RF geolocation Geolocation of RF Signals Principles and Simulations will be of interest to government agency program managers industry professionals and engineers academic researchers faculty and graduate students who are interested in or currently designing developing and deploying innovative geolocation of RF Signal systems Advances in Visual Computing George Bebis, Richard Boyle, Bahram Parvin, Darko Koracin, Ioannis Pavlidis, Rogerio Feris, Tim McGraw, Mark Elendt, Regis Kopper, Eric Ragan, Zhao Ye, Gunther Weber, 2015-12-17 The two volume set LNCS 9474 and LNCS 9475 constitutes the refereed proceedings of the 11th International Symposium on Visual Computing ISVC 2015 held in Las Vegas NV USA in December 2015 The 115 revised full papers and 35 poster papers presented in this book were carefully reviewed and selected from 260 submissions The papers are organized in topical sections Part I LNCS 9474 comprises computational bioimaging computer graphics motion and tracking segmentation recognition visualization mapping modeling and surface reconstruction advancing autonomy for aerial robotics medical imaging virtual reality observing humans spectral imaging and processing intelligent transportation systems visual perception and robotic systems Part II LNCS 9475 applications 3D computer vision computer graphics segmentation biometrics pattern recognition recognition and virtual reality **Search and Rescue Robotics** Multiple Authors, 2017-08-23 In the event of large crises earthquakes

typhoons floods a primordial task of the fire and rescue services is the search for human survivors on the incident site This is a complex and dangerous task which too often leads to loss of lives among the human crisis managers themselves This book explains how unmanned search can be added to the toolkit of the search and rescue workers offering a valuable tool to save human lives and to speed up the search and rescue process The introduction of robotic tools in the world of search and rescue is not straightforward due to the fact that the search and rescue context is extremely technology unfriendly meaning that very robust solutions which can be deployed extremely quickly are required Multiple research projects across the world are tackling this problem and in this book a special focus is placed on showcasing the results of the European Union ICARUS project on this subject The ICARUS project proposes to equip first responders with a comprehensive and integrated set of unmanned search and rescue tools to increase the situational awareness of human crisis managers so that more work can be done in a shorter amount of time The ICARUS tools consist of assistive unmanned air ground and sea vehicles equipped with victim detection sensors The unmanned vehicles collaborate as a coordinated team communicating via ad hoc cognitive radio networking To ensure optimal human robot collaboration these tools are seamlessly integrated into the command and control equipment of the human crisis managers and a set of training and support tools is provided to them in order to learn to use the ICARUS system The research leading to these results has received funding from the European Community s Seventh Framework Programme FP7 2007 2013 under grant agreement number 285417 The publishing of this book was funded by the EC FP7 Post Grant Open Access Pilot programme

Deutsche Nationalbibliografie Die deutsche Nationalbibliothek,2008 *Theory and Applications for Control of Aerial Robots in Physical Interaction Through Tethers* Marco Tognon,Antonio Franchi,2020-06-26 This book studies how autonomous aerial robots physically interact with the surrounding environment Intended to promote the advancement of aerial physical interaction it analyzes a particular class of aerial robots tethered aerial vehicles By examining specific systems while still considering the challenges of the general problem it will help readers acquire the knowledge and expertise needed for the subsequent development of more general methods applicable to aerial physical interaction The formal analysis covers topics ranging from control state estimation and motion planning to experimental validation Addressing both theoretical and technical aspects the book is intended for a broad academic and industrial readership including undergraduate students researchers and engineers It can be used as a teaching reference or as the basis for product development

Aerial Robotic Manipulation Anibal Ollero,Bruno Siciliano,2019-06-27 Aerial robotic manipulation integrates concepts and technologies coming from unmanned aerial systems and robotics manipulation It includes not only kinematic dynamics aerodynamics and control but also perception planning design aspects mechatronics and cooperation between several aerial robotics manipulators All these topics are considered in this book in which the main research and development approaches in aerial robotic manipulation are presented including the description of relevant systems In addition of the research aspects the book also includes the deployment of real systems

both indoors and outdoors which is a relevant characteristic of the book because most results of aerial robotic manipulation have been validated only indoor using motion tracking systems Moreover the book presents two relevant applications structure assembly and inspection and maintenance which has started to be applied in the industry The Chapters of the book will present results of two main European Robotics Projects in aerial robotics manipulation FP7 ARCAS and H2020 AEROARMS FP7 ARCAS defined the basic concepts on aerial robotic manipulation including cooperative manipulation The H2020 AEROARMS on aerial robot with multiple arms and advanced manipulation capabilities for inspection and maintenance has two general objectives 1 development of advanced aerial robotic manipulation methods and technologies including manipulation with dual arms and multi directional thrusters aerial platforms and 2 application to the inspection and maintenance

Visual Guidance of Unmanned Aerial Manipulators Angel Santamaria-Navarro,Joan Solà,Juan Andrade-Cetto,2018-08-18 This monograph covers theoretical and practical aspects of the problem of autonomous guiding of unmanned aerial manipulators using visual information For the estimation of the vehicle state position orientation velocity and acceleration the authors propose a method that relies exclusively on the use of low cost and highrate sensors together with low complexity algorithms This is particularly interesting for applications in which on board computation with low computation power is needed Another relevant topic covered in this monograph is visual servoing The authors present an uncalibrated visual servo scheme capable of estimating at run time the camera focal length from the observation of a tracked target The monograph also covers several control techniques which achieve a number of tasks such as robot and arm positioning improve stability and enhance robot arm motions All methods discussed in this monograph are demonstrated in simulation and through real robot experimentation The text is appropriate for readers interested in state estimation and control of aerial manipulators and is a reference book for people who work in mobile robotics research in general

Intelligent Autonomy of UAVs Yasmina Bestaoui Sebbane,2018-03-14 Intelligent Autonomy of UAVs Advanced Missions and Future Use provides an approach to the formulation of the fundamental task typical to any mission and provides guidelines of how this task can be solved by different generic robotic problems As such this book aims to provide a systems engineering approach to UAV projects discovering the real problems that need to be resolved independently of the application After an introduction to the rapidly evolving field of aerial robotics the book presents topics such as autonomy mission analysis human UAV teams homogeneous and heterogeneous UAV teams and finally UAV UGV teams It then covers generic robotic problems such as orienteering and coverage The book next introduces deployment patrolling and foraging while the last part of the book tackles an important application aerial search tracking and surveillance This book is meant for both scientists and practitioners For practitioners it presents existing solutions that are categorized according to various missions surveillance and reconnaissance 3D mapping urban monitoring precision agriculture forestry disaster assessment and monitoring security industrial plant inspection etc For scientists it provides an overview of generic robotic problems such

as coverage and orienteering deployment patrolling and foraging search tracking and surveillance The design and analysis of algorithms raise a unique combination of questions from many fields including robotics operational research control theory and computer science Unmanned Aerial Systems Anis Koubaa,Ahmad Taher Azar,2021-01-21 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 **Autonomous Control Systems and Vehicles** Kenzo Nonami,Muljowidodo Kartidjo,Kwang-Joon Yoon,Agus Budiyo,2013-05-30 The International Conference on Intelligent Unmanned Systems 2011 was organized by the International Society of Intelligent Unmanned Systems and locally by the Center for Bio Micro Robotics Research at Chiba University Japan The event was the 7th conference continuing from previous conferences held in Seoul Korea 2005 2006 Bali Indonesia 2007 Nanjing China 2008 Jeju Korea 2009 and Bali Indonesia 2010 ICIUS 2011 focused on both theory and application primarily covering the topics of robotics autonomous vehicles intelligent unmanned technologies and biomimetics We invited seven keynote speakers who dealt with related state of the art technologies including unmanned aerial vehicles UAVs and micro air vehicles MAVs flapping wings FWs unmanned ground vehicles UGVs underwater vehicles UVs bio inspired robotics advanced control and intelligent systems among others This book is a collection of excellent papers that were updated after presentation at ICIUS2011 All papers that form the chapters of this book were reviewed and revised from the perspective of advanced relevant technologies in the field The aim of this book is to stimulate interactions among researchers active in the areas pertinent to intelligent unmanned systems **Bio-inspired Computation in Unmanned Aerial Vehicles** Haibin Duan,Pei Li,2014-01-02 Bio inspired Computation in Unmanned Aerial Vehicles focuses on the aspects of path planning formation control heterogeneous cooperative control and vision based surveillance and navigation in Unmanned Aerial Vehicles UAVs from the perspective of bio inspired computation It helps readers to gain a comprehensive understanding of control related problems in UAVs presenting the latest advances in bio inspired computation By combining bio inspired computation and UAV control problems key questions are explored in depth and each piece is content rich while remaining accessible With abundant illustrations of simulation work this book links theory algorithms and implementation

procedures demonstrating the simulation results with graphics that are intuitive without sacrificing academic rigor Further it pays due attention to both the conceptual framework and the implementation procedures The book offers a valuable resource for scientists researchers and graduate students in the field of Control Aerospace Technology and Astronautics especially those interested in artificial intelligence and Unmanned Aerial Vehicles Professor Haibin Duan and Dr Pei Li both work at Beihang University formerly Beijing University of Aeronautics Astronautics BUAA Prof Duan s academic website is <http://hbduan.buaa.edu.cn>

Model-Based Control of Flying Robots for Robust Interaction Under Wind Influence Teodor Tomić,2022-10-07 This book addresses the topic of autonomous flying robots physically interacting with the environment under the influence of wind It aims to make aerial robots aware of the disturbance interaction and faults acting on them This requires reasoning about the external wrench force and torque acting on the robot and distinguishing between wind interactions and collisions The book takes a model based approach and covers a systematic approach to parameter identification for flying robots The book aims to provide a wind speed estimate independent of the external wrench including estimating the wind speed using motor power measurements Aerodynamics modeling is approached in a data driven fashion using ground truth measurements from a 4D wind tunnel Finally the book bridges the gap between trajectory tracking and interaction control to allow physical interaction under wind influence Theoretical results are accompanied by extensive simulation and experimental results

Planning and Decision Making for Aerial Robots Yasmina Bestaoui Sebbane,2014-01-10 This book provides an introduction to the emerging field of planning and decision making for aerial robots An aerial robot is the ultimate form of Unmanned Aerial Vehicle an aircraft endowed with built in intelligence requiring no direct human control and able to perform a specific task It must be able to fly within a partially structured environment to react and adapt to changing environmental conditions and to accommodate for the uncertainty that exists in the physical world An aerial robot can be termed as a physical agent that exists and flies in the real 3D world can sense its environment and act on it to achieve specific goals So throughout this book an aerial robot will also be termed as an agent Fundamental problems in aerial robotics include the tasks of spatial motion spatial sensing and spatial reasoning Reasoning in complex environments represents a difficult problem The issues specific to spatial reasoning are planning and decision making Planning deals with the trajectory algorithmic development based on the available information while decision making determines priorities and evaluates potential environmental uncertainties The issues specific to planning and decision making for aerial robots in their environment are examined in this book and categorized as follows motion planning deterministic decision making decision making under uncertainty and finally multi robot planning A variety of techniques are presented in this book and a number of relevant case studies are examined The topics considered in this book are multidisciplinary in nature and lie at the intersection of Robotics Control Theory Operational Research and Artificial Intelligence

Multi-UAV Planning and Task Allocation Yasmina Bestaoui Sebbane,2020-03-27 Multi robot systems are

a major research topic in robotics Designing testing and deploying aerial robots in the real world is a possibility due to recent technological advances This book explores different aspects of cooperation in multiagent systems It covers the team approach as well as deterministic decision making It also presents distributed receding horizon control as well as conflict resolution artificial potentials and symbolic planning The book also covers association with limited communications as well as genetic algorithms and game theory reasoning Multiagent decision making and algorithms for optimal planning are also covered along with case studies Key features Provides a comprehensive introduction to multi robot systems planning and task allocation Explores multi robot aerial planning flight planning orienteering and coverage and deployment patrolling and foraging Includes real world case studies Treats different aspects of cooperation in multiagent systems Both scientists and practitioners in the field of robotics will find this text valuable

Unmanned Aerial Vehicles Formation Control and Safety Guarantee Maolong Lv, Boyang Zhang, Haibin Duan, Yuyuan Shi, Chuhan Zhou, 2025-08-08 This book focuses on the practical challenges in the process of UAV cooperative control from three aspects the first to satisfy the task requirement of convergence time for multi UAV system the second to fit the actual capability of transmission computation and communication for multi UAV system the third to ensure safety in the presence of strong disturbances and DoS attack for multi UAV system In addition this book presents the cooperative control design from inner loop velocity and attitude tracking to outer loop position motions of multiple UAVs It offers readers with deep understanding and insights on reliability adaptability and safety of multi UAV system and the corresponding control designs The advanced cooperative control methods presented in this book can provide guidelines for engineers to improve the reliability adaptability and safety of aerospace engineering systems and some other related fields This book is suitable for scientists and researchers aerospace engineers control engineers lecturers and teachers postgraduates undergraduates in the system and control community especially those engaged in the field of UAV cooperation and multi agent systems

Autonomous Flying Robots Kenzo Nonami, Farid Kendoul, Satoshi Suzuki, Wei Wang, Daisuke Nakazawa, 2010 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 classification 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 particular UAVs have many applications in emergency situations humans often cannot come close to a dangerous natural disaster such as an earthquake a food an active volcano or a nuclear disaster Since the development of the first UAVs research efforts have been focused on military applications Recently however demand has arisen for UAVs such as aero robots and flying robots that 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 *Smart Autonomous Aircraft* Yasmina Bestaoui Sebbane,2015-11-18 With the extraordinary growth of Unmanned Aerial Vehicles UAV in research military and commercial contexts there has been a need for a reference that provides a comprehensive look at the latest research in the area Filling this void Smart Autonomous Aircraft Flight Control and Planning for UAV introduces the advanced methods of flight contr

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