
Directed Sonar Sensing for Mobile Robot Navigation

John J. Leonard
Hugh F. Durrant-Whyte



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J. O. Gray, Darwin G. Caldwell



Directed Sonar Sensing For Mobile Robot Navigation:

Directed Sonar Sensing for Mobile Robot Navigation John J. Leonard, Hugh F. Durrant-Whyte, 2012-12-06 This monograph is a revised version of the D Phil thesis of the first author submitted in October 1990 to the University of Oxford. This work investigates the problem of mobile robot navigation using sonar. We view model based navigation as a process of tracking naturally occurring environment features which we refer to as targets. Targets that have been predicted from the environment map are tracked to provide that are observed but not predicted vehicle position estimates. Targets represent unknown environment features or obstacles and cause new tracks to be initiated, classified and ultimately integrated into the map. Chapter 1 presents a brief definition of the problem and a discussion of the basic research issues involved. No attempt is made to survey exhaustively the mobile robot navigation literature; the reader is strongly encouraged to consult other sources. The recent collection edited by Cox and Wilfong [34] is an excellent starting point as it contains many of the standard works of the field. Also we assume familiarity with the Kalman filter. There are many well known texts on the subject; our notation derives from Bar Shalom and Fortmann [7]. Chapter 2 provides a detailed sonar sensor model. A good sensor model of our approach to navigation and is used both for is a crucial component predicting expected observations and classifying unexpected observations.

Efficient Dynamic Simulation of Robotic Mechanisms Kathryn Lilly, 2012-12-06 Efficient Dynamic Simulation of Robotic Mechanisms presents computationally efficient algorithms for the dynamic simulation of closed chain robotic systems. In particular the simulation of single closed chains and simple closed chain mechanisms is investigated in detail. Single closed chains are common in many applications including industrial assembly operations, hazardous remediation and space exploration. Simple closed chain mechanisms include such familiar configurations as multiple manipulators moving a common load, dexterous hands and multi legged vehicles. The efficient dynamics simulation of these systems is often required for testing an advanced control scheme prior to its implementation to aid a human operator during remote teleoperation or to improve system performance. In conjunction with the dynamic simulation algorithms, efficient algorithms are also derived for the computation of the joint space and operational space inertia matrices of a manipulator. The manipulator inertia matrix is a significant component of any robot dynamics formulation and plays an important role in both simulation and control. The efficient computation of the inertia matrix is highly desirable for real time implementation of robot dynamics algorithms. Several alternate formulations are provided for each inertia matrix. Computational efficiency in the algorithm is achieved by several means including the development of recursive formulations and the use of efficient spatial transformations and mathematics. All algorithms are derived and presented in a convenient tabular format using a modified form of spatial notation, a six dimensional vector notation which greatly simplifies the presentation and analysis of multibody dynamics. Basic definitions and fundamental principles required to use and understand this notation are provided. The implementation of the efficient spatial transformations is also discussed in some

detail As a means of evaluating efficiency the number of scalar operations multiplications and additions required for each algorithm is tabulated after its derivation Specification of the computational complexity of each algorithm in this manner makes comparison with other algorithms both easy and convenient The algorithms presented in Efficient Dynamic Simulation of Robotic Mechanisms are among the most efficient robot dynamics algorithms available at this time In addition to computational efficiency special emphasis is also placed on retaining as much physical insight as possible during algorithm derivation The algorithms are easy to follow and understand whether the reader is a robotics novice or a seasoned specialist

Advanced Robotics & Intelligent Machines J. O. Gray, Darwin G. Caldwell, 1996 Advanced robotics describes the use of sensor based robotic devices which exploit powerful computers to achieve the high levels of functionality that begin to mimic intelligent human behaviour The object of this book is to summarise developments in the base technologies survey recent applications and highlight new advanced concepts which will influence future progress Sensor Modelling, Design and Data Processing for Autonomous Navigation Martin David Adams, 1999 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 **New Concepts and Applications in Soft Computing**

Valentina Emilia Balas, János Fodor, Annamária R. Várkonyi-Kóczy, 2012-07-20 The book provides a sample of research on the innovative theory and applications of soft computing paradigms The idea of Soft Computing was initiated in 1981 when Professor Zadeh published his first paper on soft data analysis and constantly evolved ever since Professor Zadeh defined Soft Computing as the fusion of the fields of fuzzy logic FL neural network theory NN and probabilistic reasoning PR with the latter subsuming belief networks evolutionary computing including DNA computing chaos theory and parts of learning theory into one multidisciplinary system As Zadeh said the essence of soft computing is that unlike the traditional hard computing soft computing is aimed at an accommodation with the pervasive imprecision of the real world Thus the guiding principle of soft computing is to exploit the tolerance for imprecision uncertainty and partial truth to achieve tractability robustness low solution cost and better rapport with reality In the final analysis the role model for soft computing is the human mind We hope that the reader will share our excitement and find our volume both useful and inspiring Field and Service Robotics Alexander Zelinsky, 2012-12-06 Joe Engelberger the pioneer of the robotics industry wrote in his 1989 book Robotics in

Service that the inspiration to write his book came as a reaction to an industry sponsored forecast study of robot applications which predicted that in 1995 applications of robotics outside factories the traditional domain of industrial robots would amount to less than 1% of total sales Engelberger believed that this forecast was very wrong and instead predicted that the non industrial class of robot applications would become the largest class Engelbergers prediction has yet to come to pass However he did correctly foresee the growth in non traditional applications of robots Robots are now beginning to march from the factories and into field and service applications This book presents a selection of papers from the first major international conference dedicated to field and service applications of robotics This selection includes papers from the leading research laboratories in the world together with papers from companies that are building and selling new and innovative robotic technology It describes interesting aspects of robots in the field ranging from mining agriculture construction cargo handling subsea operations removal of landmines to terrestrial exploration It also covers a diverse range of service applications such as cleaning propagating plants and aiding the elderly and handicapped and gives considerable attention to the technology required to realise robust reliable and safe robots

Soft Computing and Industry Rajkumar Roy, Mario Köppen, Seppo Ovaska, Takeshi Furuhashi, Frank Hoffmann, 2012-12-06 Soft computing embraces various methodologies for the development of intelligent systems that have been successfully applied to a large number of real world problems Soft Computing in Industry contains a collection of papers that were presented at the 6th On line World Conference on Soft Computing in Industrial Applications that was held in September 2001 It provides a comprehensive overview of recent theoretical developments in soft computing as well as of successful industrial applications It is divided into seven parts covering material on keynote papers on various subjects ranging from computing with autopoietic systems to the effects of the Internet on education intelligent control classification clustering and optimization image and signal processing agents multimedia and Internet theoretical advances prediction design and diagnosis The book is aimed at researchers and professional engineers who develop and apply intelligent systems in computer engineering

Sensor Fusion and Decentralized Control in Robotic Systems, 2001

Intelligent Autonomous Systems Ulrich Rembold, 1995 This text presents the proceedings of a conference on intelligent autonomous systems Papers contribute solutions to the task of designing autonomous systems that are capable of operating independently of a human in partially structured and unstructured environments For specific application these systems should also learn from their actions in order to improve and optimize planning and execution of new tasks

Intelligent Control Systems and Signal Processing 2003 M. G. Ruano, António E. Ruano, Peter J. Fleming, 2003 KEY FEATURES The first IFAC conference and thus proceedings to be specifically devoted to this field Presents the findings of experts and practitioners from the major soft computing themes Provides an overview of the theory and applications of intelligent control systems and signal processing Intelligent control systems and signal processing 2003 contains the selection of papers presented at the IFAC International Conference on

Intelligent Control systems and Signal Processing ICONS 2003 The conference was sponsored by the most important organizations in the field among them were the Institute of Electrical and Electronic Engineers IEEE and the Control Systems Society CSS This proceedings volume contains 98 papers with three separate reviewers having reviewed all papers Including six plenary lectures given by leading experts in the field

From Animals to Animats 5 Rolf Pfeifer, 1998 The Animals to Animats Conference brings together researchers from ethology psychology ecology artificial intelligence artificial life robotics engineering and related fields to further understanding of the behaviors and underlying mechanisms that allow natural and synthetic agents animats to adapt and survive in uncertain environments The Animals to Animats Conference brings together researchers from ethology psychology ecology artificial intelligence artificial life robotics engineering and related fields to further understanding of the behaviors and underlying mechanisms that allow natural and synthetic agents animats to adapt and survive in uncertain environments The work presented focuses on well defined models robotic computer simulation and mathematical that help to characterize and compare various organizational principles or architectures underlying adaptive behavior in both natural animals and animats

Fuzzy Navigation System for Mobile Robots in Construction Seung-ho Lee, 1995

Analysis of Internal Wave Induced Mode Coupling Effects on the 1995 SWARM Experiment Acoustic Transmissions Robert Hugh Headrick, 1997 As part of the Shallow Water Acoustics in a Random Medium SWARM experiment 1 a sixteen element WHOI vertical line array WVLA was moored in 70 meters of water off the New Jersey coast This array was sampled at 1395 Hz or higher for the seven days it was deployed Tomography sources with carrier frequencies of 224 and 400 Hz were moored about 32 km shoreward such that the acoustic path was anti parallel to the primary propagation direction for shelf generated internal wave solitons Two models for the propagation of normal modes through a 2 D waveguide with solitary internal wave soliton scattering included are developed to help in understanding the very complicated mode arrivals seen at the WVLA The simplest model uses the Preisig and Duda 2 sharp interface approximation for solitons allowing for rapid analysis of the effects of various numbers of solitons on mode arrival statistics The second model using SWARM thermistor string data to simulate the actual SWARM waveguides is more realistic but much slower The analysis of the actual WVLA data yields spread bias wander and intensity fluctuation signals that are modulated at tidal frequencies The signals are consistent with predicted relationships to the internal wave distributions in the waveguides

Mobile Robot Localization Using Pattern Classification Techniques Jonathan D. Courtney, 1993

An Entropic Framework for AUV Sensor Modelling Hanumant Singh, 1995 This thesis examines the general task of active sensing by defining a measure of efficiency for sensing in a particular environment We focus on fine scale acoustic mapping from an autonomous underwater vehicle AUV The constraints on imaging underwater vehicle power vehicle hydrodynamics computational and telemetry requirements and typical navigational and attitudinal uncertainties along with the underlying physics of the acoustic sensing modality are considered in defining an entropic measure of sensor efficiency 675 kHz pencil

beam sonar data acquired using the JASON remotely operated vehicle in a challenging shallow water environment and 200 kHz echo sounder data acquired using the ABE AUV are used to demonstrate the utility of the entropic framework. We show the utility of an entropic framework for the following: i) Optimizing the speed of the AUV for maximizing the information gathered with a particular sensor; ii) the rate of convergence and the stability of our mapping efforts in the face of typical uncertainties in navigation and attitude; iii) as a methodology for actual sensor deployment and use on a real vehicle; and iv) in tasks such as post mission analysis for applications such as change detection and path planning for subsequent missions.

Oceans '94, 1994 **Sensor Fusion and Decentralized Control in Robotic Systems II** G. T. McKee, Paul S.

Schenker, 1999 This work presents a series of papers examining various aspects of sensor fusion and decentralized control in robotic systems **Intelligent Robots and Computer Vision**, 1999 *Proceedings of the ... ASME Design Engineering*

Technical Conferences, 2006 **Motion Estimation of Distributed Objects Using Doppler** Rockie L. Ricks, 1994

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