

World Scientific Series in Robotics and Automated Systems – Vol. 2

PARALLEL COMPUTATION SYSTEMS FOR ROBOTICS

Algorithms and Architectures

edited by

A. Fijany and A. Bejczy

World Scientific

Parallel Computation Systems For Robotics Algorithms And Architectures

National Science Foundation (U.S.)



Parallel Computation Systems For Robotics Algorithms And Architectures:

Parallel Computation Systems For Robotics: Algorithms And Arch. Amir Fijany, Antal K Bejczy, 1992-08-31 This book presents an extensive survey of the state of the art research in parallel computational algorithms and architectures for robot manipulator control and simulation. It deals not only with specifics but also includes general and broader issues which serve as a useful foundation to the topic. The educational flavor of the book makes it a necessary resource for researchers, engineers, and students wanting to be familiarized with the potential offered by the application of parallel processing to robotic problems and its current issues and trends.

Parallel Computation Systems for Robotics A. Fijany, A. Bejczy, 1992 Applied Parallel Computing Yuefan Deng, 2013 The book provides a practical guide to computational scientists and engineers to help advance their research by exploiting the superpower of supercomputers with many processors and complex networks. This book focuses on the design and analysis of basic parallel algorithms, the key components for composing larger packages for a wide range of applications.

Algorithms and Architectures for Real-Time Control 1992 P.J. Fleming, W.H. Kwon, 2014-05-23 This Workshop focuses on such issues as control algorithms which are suitable for real time use, computer architectures which are suitable for real time control algorithms and applications for real time control issues in the areas of parallel algorithms, multiprocessor systems, neural networks, fault tolerance systems, real time robot control, identification, real time filtering, algorithms, control algorithms, fuzzy control, adaptive and self tuning control, and real time control applications.

Sensor-Based Robots: Algorithms and Architectures C.S. George Lee, 2012-12-06 Most industrial robots today have little or no sensory capability. Feedback is limited to information about joint positions combined with a few interlock and timing signals. These robots can function only in an environment where the objects to be manipulated are precisely located in the proper position for the robot to grasp, i.e. in a structured environment. For many present industrial applications, this level of performance has been adequate. With the increasing demand for high performance sensor based robot manipulators in assembly tasks, meeting this demand and challenge can only be achieved through the consideration of 1 efficient acquisition and processing of internal/external sensory information, 2 utilization and integration of sensory information from various sensors (tactile force and vision) to acquire knowledge in a changing environment, 3 exploitation of inherent robotic parallel algorithms and efficient VLSI architectures for robotic computations, and finally 4 system integration into a working and functioning robotic system. This is the intent of the Workshop on Sensor Based Robots: Algorithms and Architectures to study the fundamental research issues and problems associated with sensor based robot manipulators and to propose approaches and solutions from various viewpoints in improving present day robot manipulators in the areas of sensor fusion and integration, sensory information processing, and parallel algorithms and architectures for robotic computations.

Scientific and Technical Aerospace Reports, 1994

Control and Dynamic Systems V40: Advances in Robotic Systems Part 2 of 2 C.T. Leonides, 2012-12-02 Advances

in Robotic Systems Part 2 is the second of a companion set of two volumes on advances in robotic systems dynamics and control This book comprises nine chapters with the first focusing on kinesthetic feedback techniques in teleoperated systems The succeeding chapters then delve into topics such as parallel algorithms and fault tolerant reconfigurable architecture for robot kinematics and dynamics computations trajectory planning for robot control and a control systems perspective Other chapters cover simplified techniques for adaptive control of robotic systems theory and applications of configuration control for redundant manipulators nonlinear feedback for force control of robot manipulators systolic architectures for dynamic control of manipulators inverse dynamics and forward dynamics This book will be of interest to practitioners in the fields of computer science systems science and mathematics Study and Research Guide in Computer Science Wolfgang Tölle,Jason Yasner,Michael Pieper,2012-12-06 Computer science departments at universities in the U S A are world renowned This handy reference guide gives detailed profiles of 40 of the best known among them The profiles are organized in a uniform layout to present basic information faculty curriculum courses for graduate students affiliated institutions facilities research areas funding selected projects and collaborations Two full alphabetical listings of professors are included one giving their universities and the other their research areas The guide will be indispensable for anyone student or faculty not only in the U S A interested in research and education in computer science in the U S A **ISIE ...** ,1997

Encyclopedia of Computer Science and Technology Allen Kent,James G. Williams,1992-03-20 This comprehensive reference work provides immediate fingertip access to state of the art technology in nearly 700 self contained articles written by over 900 international authorities Each article in the Encyclopedia features current developments and trends in computers software vendors and applications extensive bibliographies of leading figures in the field such as Samuel Alexander John von Neumann and Norbert Wiener and in depth analysis of future directions *International Books in Print*, 1995 Barbara Hopkinson,[Anonymus AC01401231],1995 **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 *Romansy 14* Giovanni Bianchi, Jean-Claude Guinot, Cezary Rzymkowski, 2003-05-06 *Mechanics Motion Control Sensing and Programming Synthesis and Design Legged Locomotion and Biomechanical Aspects of Robots and Manipulators* world view of the state of the art *Characterization* This volume presents the latest contribution to the theory and practice of modern robotics given by the world recognized scientists from Australia Canada Europe Japan Mexico Singapore and USA Guide to Programs National Science Foundation (U.S.), *Architecture of Computing Systems - ARCS 2018* Mladen Berekovic, Rainer Buchty, Heiko Hamann, Dirk Koch, Thilo Pionteck, 2018-04-05 This book constitutes the proceedings of the 31st International Conference on Architecture of Computing Systems ARCS 2018 held in Braunschweig Germany in April 2018 The 23 full papers presented in this volume were carefully reviewed and selected from 53 submissions ARCS has always been a conference attracting leading edge research outcomes in Computer Architecture and Operating Systems including a wide spectrum of topics ranging from embedded and real time systems all the way to large scale and parallel systems **Forthcoming Books** Rose Arny, 1992-10

Fuzzy Logic Control H. B. Verbruggen, Robert Babuška, 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 Proceedings of the IEEE International Symposium on Industrial Electronics ,1997 *NASA Tech Briefs* ,1991 *High-Level Feedback Control with Neural Networks* Young Ho Kim, Frank L. Lewis, 1998 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

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