

COMPUTER ARCHITECTURES FOR ROBOTICS AND AUTOMATION

Edited by JAMES H. GRAHAM

Specialized Computer Architectures For Robotics And Automation

**Chris A. Vissers, Luís Ferreira
Pires, Dick A.C. Quartel, Marten van
Sinderen**

Specialized Computer Architectures For Robotics And Automation:

Computer Architectures for Robotics and Automation James H. Graham,1987 Addresses the important topic of providing adequate computational power for the demanding real time requirements of advanced robotic systems Shows how many of the recent advances in image processing control and machine intelligence can be incorporated into robotic systems in real time Explains how innovative specialized computer architectures that include both parallelism and special purpose hardware can speed the development of robot potential *Workshop on Special Computer Architectures for Robotics and Automation* IEEE Robotics and Automation Council,1985 *Distributed Autonomous Robotic Systems 3* Tim Lueth,Rüdiger

Dillmann,Paolo Dario,Heinz Wörn,2012-12-06 Distributed autonomous robotic systems DARS are systems composed of multiple autonomous units such as modules cells processors agents and robots Combination or cooperative operation of multiple autonomous units is expected to lead to desirable features such as flexibility fault tolerance and efficiency The DARS is the leading established conference on distributed autonomous systems All papers have the common goal to contribute solutions to the very demanding task of designing distributed systems to realize robust and intelligent robotic systems

Architectural Design Chris A. Vissers,Luís Ferreira Pires,Dick A.C. Quartel,Marten van Sinderen,2016-09-30 This book presents a design methodology that is practically applicable to the architectural design of a broad range of systems It is based on fundamental design concepts to conceive and specify the required functional properties of a system while abstracting from the specific implementation functions and technologies that can be chosen to build the system Abstraction and precision are indispensable when it comes to understanding complex systems and precisely creating and representing them at a high functional level Once understood these concepts appear natural self evident and extremely powerful since they can directly precisely and concisely reflect what is considered essential for the functional behavior of a system The first two chapters present the global views on how to design systems and how to interpret terms and meta concepts This informal introduction provides the general context for the remainder of the book On a more formal level Chapters 3 through 6 present the main basic design concepts illustrating them with examples Language notations are introduced along with the basic design concepts Lastly Chapters 7 to 12 discuss the more intricate basic design concepts of interactive systems by focusing on their common functional goal These chapters are recommended to readers who have a particular interest in the design of protocols and interfaces for various systems The didactic approach makes it suitable for graduate students who want to develop insights into and skills in developing complex systems as well as practitioners in industry and large organizations who are responsible for the design and development of large and complex systems It includes numerous tangible examples from various fields and several appealing exercises with their solutions **Workshop on Special Computer**

Architectures for Robotics James Urey Korein,Damian M. Lyons,Gerry Pocock,IEEE Robotics and Automation Council,1988

Recent Trends in Mobile Robots Yuan-Fang Zheng,1993 This book presents recent trends in the field as perceived by

a global selection of researchers and experts Subjects covered include motion planning of mobile robots in unknown environments coordination between mobility and manipulability computation environments for mobile robots nonlinear control of mobile robots and environmental modeling using advanced sensing technologies Issues ranging from progress in applications to fundamental problems are discussed

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 intemaVextemal 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 manipula tors in the areas of sensor fusion and integration sensory information processing and parallel algorithms and architectures for robotic computations

1993 Computer Architectures for Machine Perception Magdy A. Bayoumi,Larry S. Davis,Kimon Valavanis,1993 Proceedings of the Computer Architectures for Machine Perception Workshop held Dec 15 17 1993 in New Orleans Louisiana Papers came from several communities computer architecture pattern recognition image processing and analysis computer vision and VLSI No index Annotation copyright Book N

Modelling and Identification in Robotics Krzysztof R. Kozlowski,2012-12-06 As the use and relevance of robotics for countless scientific purposes grows all the time research into the many diverse elements of the subject becomes ever more important and in demand This volume examines in depth the most topical complex issues of modelling and identification in robotics The book is divided into three main parts The first part is devoted to robot dynamics modelling and identification of robot and load parameters incorporating friction torques discussing identification schemes and presenting simulations and experiment al results of robot and load dynamic parameters identification A general concept of robot programming language for research and educational purposes is examined and there is a detailed outline of its basic structures along with hardware requirements which both constitute an open robot controller architecture Finally a hybrid controller is derived and several experimental results of this system are outlined This impressive discussion of the topic covers both the theoretical and practical illustrated throughout by examples and experimental results and will be of value to anyone researching or practising within the field of

robotics automation and system identification or to control engineers **Parallel and Distributed Computing Handbook**
Albert Y. Zomaya,1996 With over 1 000 pages and a wealth of illustrations and data tables this handbook offers readers the
first information source with the scope to encompass the parallel and distributed computing revolution Written by an
international team of experts the book summarizes the current state of the art interprets the most promising trends and
spotlights commercial applications Robotics Abstracts ,1990 Architectural Alternatives for Exploiting Parallelism
David J. Lilja,1991 Graduates advanced undergraduates and practicing engineers of computer architecture or system design
may find interest in the survey of various architectures within which a computer can be induced to walk and chew gum at the
same time The 37 reprinted journal articles and conference presentation **NBS Special Publication** ,1968 Fourth
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Jabbour,1988 *Cooperative Intelligent Robotics in Space* ,1992 **Cooperative Intelligent Robotics in Space III** Jon
D. Erickson,1992 **1986 IEEE Workstation Technology & Systems Conference** ,1986 Supercomputing Systems
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