A First Look At Graph Theory

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the slumdog phenomenon addresses multiple issues related to slumdog millionaire and in the process provides new ways of looking at this controversial film each of the book s four sections considers a particular aspect of the film its relation to the nation to the slum to bollywood and its reception the volume provides a critical overview of the key issues and debates stemming from the film and allows readers to reexamine them in light of the anthology s multiple perspectives

exploring artificial intelligence survey talks from the national conference on artificial intelligence provides information pertinent to the distinct subareas of artificial intelligence research this book discusses developments in machine learning techniques organized into six parts encompassing 16 chapters this book begins with an overview of intelligent tutoring systems which describes how to guide a student to learn new concepts this text then links closely with one of the concerns of intelligent tutoring systems namely how to interact through the utilization of natural language other chapters consider the various aspects of natural language understanding and survey the huge body of work that tries to characterize heuristic search programs this book discusses as well how computer

programs can create plans to satisfy goals the final chapter deals with computational facilities that support this book is a valuable resource for cognitive scientists psychologists domain experts computer scientists instructional designers expert teachers and research workers

constraint reasoning has matured over the last three decades with contributions from a diverse community of researchers in artificial intelligence databases and programming languages operations research management science and applied mathematics in constraint processing rina dechter synthesizes these contributions as well as her own significant work to provide the first comprehensive examination of the theory that underlies constraint processing algorithms

search has been vital to artificial intelligence from the very beginning as a core technique in problem solving the authors present a thorough overview of heuristic search with a balance of discussion between theoretical analysis and efficient implementation and application to real world problems current developments in search such as pattern databases and search with efficient use of external memory and parallel processing units on main boards and graphics cards are detailed heuristic search as a problem solving tool is demonstrated in applications for puzzle solving game playing constraint satisfaction and machine learning while no previous familiarity with heuristic search is necessary the reader should have a basic knowledge of algorithms data structures and calculus real world case studies and chapter ending exercises help to create a full and realized picture of how search fits into the world of artificial intelligence and the one around us provides real world success stories and case studies for heuristic search algorithms includes many ai developments not yet covered in textbooks such as pattern databases symbolic search and parallel processing units

during the last decades improved sensor and hardware technologies as well as new methods and algorithms have made self driving vehicles a realistic possibility in the near future thanks to this technology enhancement many leading automotive and technology companies have turned their attention towards developing advanced driver assistance systems adas and self driving vehicles autonomous vehicles are expected to have their first big impact in closed areas such as mines harbors and loading offloading sites in such areas the legal requirements are less restrictive and the surrounding environment is more controlled and predictable compared to urban areas expected positive outcomes include increased productivity and safety reduced emissions and the possibility to relieve the human from performing complex or dangerous tasks within these sites different truck and trailer systems are used to transport materials these systems are composed of several interconnected modules and are thus large and highly unstable while reversing this thesis addresses the problem of designing efficient motion planning and feedback control frameworks for such systems first a cascade controller for a reversing truck with a dolly steered trailer is presented the unstable modes of the system is stabilized around circular

equilibrium configurations using a gain scheduled linear quadratic lq controller together with a higher level pure pursuit controller to enable path following of piecewise linear reference paths the cascade controller is then used within a rapidly exploring random tree rrt framework and the complete motion planning and control framework is demonstrated on a small scale test vehicle second a path following controller for a reversing truck with a dolly steered trailer is proposed for the case when the obtained motion plan is kinematically feasible the control errors of the system are modeled in terms of their deviation from the nominal path and a stabilizing lq controller with feedforward action is designed based on the linearization of the control error model stability of the closed loop system is proven by combining global optimization theory from linear differential inclusions and linear matrix inequality techniques third a systematic framework is presented for analyzing stability of the closed loop system consisting of a controlled vehicle and a feedback controller executing a motion plan computed by a lattice planner when this motion planner is considered it is shown that the closed loop system can be modeled as a nonlinear hybrid system based on this a novel method is presented for analyzing the behavior of the tracking error how to design the feedback controller and how to potentially impose constraints on the motion planner in order to guarantee that the tracking error is bounded and decays towards zero fourth a complete motion planning and control solution for a truck with a dolly steered trailer is presented a lattice based motion planner is proposed where a novel parametrization of the vehicle s state space is proposed to improve online planning time a time symmetry result is established that enhance the numerical stability of the numerical optimal control solver used for generating the motion primitives moreover a nonlinear observer for state estimation is developed which only utilizes information from sensors that are mounted on the truck making the system independent of additional trailer sensors the proposed framework is implemented on a full scale truck with a dolly steered trailer and results from a series of field experiments are presented

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