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[Quad Rotorcraft Control](#) Apr 17 2021 Quad Rotorcraft Control develops original control methods for the navigation and hovering flight of an autonomous mini-quad-rotor robotic helicopter. These methods use an imaging system and a combination of inertial and altitude sensors to localize and guide the movement of the unmanned aerial vehicle relative to its immediate environment. The history, classification and applications of UAVs are introduced, followed by a description of modelling techniques for quad-rotors and the experimental platform itself. A control strategy for the improvement of attitude stabilization in quad-rotors is then proposed and tested in real-time experiments. The strategy, based on the use low-cost components and with experimentally-established robustness, avoids drift in the UAV's angular position by the addition of an internal control loop to each electronic speed controller ensuring that, during hovering flight, all four motors turn at almost the same speed. The quad-rotor's Euler angles being very close to the origin, other sensors like GPS or image-sensing equipment can be incorporated to perform autonomous positioning or trajectory-tracking tasks. Two vision-based strategies, each designed to deal with a specific kind of mission, are introduced and separately tested. The first stabilizes the quad-rotor over a landing pad on the ground; it extracts the 3-dimensional position using homography estimation and derives translational velocity by optical flow calculation. The second combines colour-extraction and line-detection algorithms to control the quad-rotor's 3-dimensional position and achieves forward velocity regulation during a road-following task. In order to estimate the translational-dynamical characteristics of the quad-rotor (relative position and translational velocity) as they evolve within a building or other unstructured, GPS-deprived environment, imaging, inertial and altitude sensors are combined in a state observer. The text give the reader a current view of the problems encountered in UAV control, specifically those relating to quad-rotor flying machines and it will interest researchers and graduate students working in that field. The vision-based control strategies presented help the reader to a better understanding of how an imaging system can be used to obtain the information required for performance of the hovering and navigation tasks ubiquitous in rotated UAV operation.

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[Velodrome Racing and the Rise of the Motorcycle](#) Feb 13 2021 A hybrid machine--powered at times by steam, electricity or internal combustion--the motorcycle in its infancy was an innovation to help bicycle racers go faster. As motor age technology advanced, the quest for greater speed at the velodrome peaked, with riders reaching speeds up to 100 kph on bikes and trikes without brakes, suspensions or gear boxes. This book chronicles the individuals and events at the turn of the 20th century that led to the development of motor-powered two-wheelers.

[New York Uninsured and Underinsured Motorist Law & Practice](#) May 19 2021 This publication provides the most comprehensive, up-to-date, and helpful guide ever written on the complex, heavily litigated, ever-changing, important, and potentially quite lucrative area of insurance law on issues involving Uninsured Motorist, Underinsured Motorist and Supplementary Uninsured/Underinsured Motorist insurance coverage. It provides clarity in this confusing area of insurance law for attorneys, insurance company claims personnel and executives, arbitrators and judges. This publication features: • Hundreds of pages of discussion and in-depth analysis • Over 5,800 citations to pertinent case law • Approximately 600 citations to the applicable statutes and regulations • Approximately 400 citations to relevant treatises and published articles • More than 70 citations to the governing arbitration rules • 55 "Practice Pointers" for practitioners • A concluding chapter comprised of forms, charts, rules and regulations all of which are to be updated annually.

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