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this chapter presents an image based proportional integral derivative pid controller for a redundant overactuated planar parallel robot the control objective is to drive the robot end effector to a desired constant reference position

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preface 2 combinatorial analysis an important problem solving skill is the ability to count or enumerate objects the discussion of enumeration in this book begins with the basic techniques of counting

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progress on questions that appear at first purely mathematical such as the onsager conjecture minimal smoothness for conservation of energy in the euler equations can provide insights towards foundations of the classical theory of turbulence namely the dissipation anomaly finite energy dissipation in the limit of zero viscosity

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time series are ubiquitous in all domains of
human endeavor they are generated stored and
manipulated during any kind of activity the goal
of this chapter is to introduce a novel approach
to mine multidimensional time series data for
causal relationships

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viii preface systems and deep learning systems we emphasize learning both as a construction method for competent systems and as a way of extending the reach of the designer into unknown environments we treat robotics and vision not as independently defined problems but as occurring in the service of achieving goals

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thread 3 algorithmic learning for resilient adaptive technologies the objective of this thread is to engineer learning algorithms based on theories and models of biological learning guided by ideas and findings as elucidated in thread 1