

Automatic Guided Vehicle Simulation in MATLAB by Using Genetic Algorithm

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1. Introduction

The prodigious advances in robotics in recent times made the use of robots more present in modern society. One important advance that requires special attention is the development of an unmanned aerial vehicle (UAV), which allows an aircraft to fly without having a human crew on board, although the UAVs still need to be controlled by a pilot or a navigator.

Today's UAVs often combine remote control and computerized automation in a manner that built-in control and/or guidance systems performs deeds like speed control and flight-path stabilization. In this sense, existing UAVs are not truly autonomous, mostly because air-vehicle autonomy field is a recently emerging field, and this could be a bottleneck for future UAV development.

It could be said that the ultimate goal in the autonomy technology development is to replace human pilots by altering machines decisions in order to make decisions like humans do. For this purpose, several tools related with artificial intelligence could be employed such as expert systems, neural networks, machine learning and natural language processing (HAYKIN, 2009). Nowadays, the field of autonomy has mostly been following a bottom-up approach, such as hierarchical control systems (SHIM, 2000).

One interesting methodology from the hierarchical control systems approach is the subsumption architecture that decomposes complicated intelligent behavior into many "simple" behavior modules, which are organized into layers. Each layer implements a particular goal and higher layers are increasingly more abstract. The decisions are not taken by a superior layer, but by listening to the information that are triggered by sensory inputs (lowest layer). This methodology allows the use of reinforcement learning to acquire behavior with the information that comes with experience.

Inspired by old behaviorist psychology, reinforcement learning (RL) concerned with how an agent ought to take actions in an environment, so as to maximize some notion of cumulative reward. Reinforcement learning differs from standard supervised learning in that correct input/output pairs which are never presented (HAYKIN, 2009). Furthermore, there is a focus on an on-line performance, which involves finding a balance between exploration (of uncharted territory) and exploitation (of current knowledge). The reinforcement learning has been applied successfully to various problems, including robot control, elevator scheduling, telecommunications, backgammon and chess (SHIM, 2000).

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Table of Contents Automatic Guided Vehicle Simulation In Matlab By Using

1. Understanding the eBook Automatic Guided Vehicle Simulation In Matlab By Using
 - The Rise of Digital Reading Automatic Guided Vehicle Simulation In Matlab By Using
 - Advantages of eBooks Over Traditional Books
2. Identifying Automatic Guided Vehicle Simulation In Matlab By Using
 - Exploring Different Genres
 - Considering Fiction vs. Non-Fiction
 - Determining Your Reading Goals
3. Choosing the Right eBook Platform
 - Popular eBook Platforms
 - Features to Look for in an Automatic Guided Vehicle Simulation In Matlab By Using
 - User-Friendly Interface
4. Exploring eBook Recommendations from Automatic Guided Vehicle Simulation In Matlab By Using
 - Personalized Recommendations
 - Automatic Guided Vehicle Simulation In Matlab By Using User Reviews and Ratings
 - Automatic Guided Vehicle Simulation In Matlab By Using and Bestseller Lists
5. Accessing Automatic Guided Vehicle Simulation In Matlab By Using Free and Paid eBooks
 - Automatic Guided Vehicle Simulation In Matlab By Using Public Domain eBooks
 - Automatic Guided Vehicle Simulation In Matlab By Using eBook Subscription Services
 - Automatic Guided Vehicle Simulation In Matlab By Using Budget-Friendly Options
6. Navigating Automatic Guided Vehicle Simulation In Matlab By Using eBook Formats

- ePub, PDF, MOBI, and More
 - Automatic Guided Vehicle Simulation In Matlab By Using Compatibility with Devices
 - Automatic Guided Vehicle Simulation In Matlab By Using Enhanced eBook Features
7. Enhancing Your Reading Experience
 - Adjustable Fonts and Text Sizes of Automatic Guided Vehicle Simulation In Matlab By Using
 - Highlighting and Note-Taking Automatic Guided Vehicle Simulation In Matlab By Using
 - Interactive Elements Automatic Guided Vehicle Simulation In Matlab By Using
 8. Staying Engaged with Automatic Guided Vehicle Simulation In Matlab By Using
 - Joining Online Reading Communities
 - Participating in Virtual Book Clubs
 - Following Authors and Publishers Automatic Guided Vehicle Simulation In Matlab By Using
 9. Balancing eBooks and Physical Books Automatic Guided Vehicle Simulation In Matlab By Using
 - Benefits of a Digital Library
 - Creating a Diverse Reading Collection Automatic Guided Vehicle Simulation In Matlab By Using
 10. Overcoming Reading Challenges
 - Dealing with Digital Eye Strain
 - Minimizing Distractions
 - Managing Screen Time
 11. Cultivating a Reading Routine Automatic Guided Vehicle Simulation In Matlab By Using
 - Setting Reading Goals Automatic Guided Vehicle Simulation In Matlab By Using
 - Carving Out Dedicated Reading Time
 12. Sourcing Reliable Information of Automatic Guided Vehicle Simulation In Matlab By Using
 - Fact-Checking eBook Content of Automatic Guided Vehicle Simulation In Matlab By Using
 - Distinguishing Credible Sources
 13. Promoting Lifelong Learning
 - Utilizing eBooks for Skill Development
 - Exploring Educational eBooks
 14. Embracing eBook Trends
 - Integration of Multimedia Elements
 - Interactive and Gamified eBooks

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