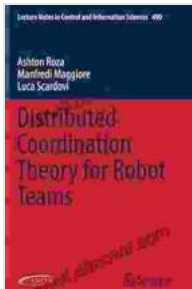


# Distributed Coordination Theory For Robot Teams: Lecture Notes In Control And

**Distributed Coordination Theory For Robot Teams: Lecture Notes In Control And** is a comprehensive guide to the latest research in distributed coordination theory for robot teams. This book presents a unified framework for analyzing and designing distributed coordination algorithms for robot teams, and provides a detailed overview of the state-of-the-art in this rapidly growing field.



## Distributed Coordination Theory for Robot Teams (Lecture Notes in Control and Information Sciences

**Book 490)** by Heather Lehr Wagner

★★★★★ 5 out of 5

Language : English  
File size : 33254 KB  
Text-to-Speech : Enabled  
Enhanced typesetting : Enabled  
Word Wise : Enabled  
Screen Reader : Supported  
Print length : 249 pages



The book begins with an to the basic concepts of distributed coordination theory, including the different types of coordination problems, the different types of robot teams, and the different types of coordination algorithms. The book then provides a detailed overview of the state-of-the-art in distributed coordination theory, including the latest research on topics such as:

- Swarm robotics
- Multi-agent systems
- Cooperative control
- Networked control systems

The book concludes with a discussion of the future directions of research in distributed coordination theory for robot teams. This book is a valuable resource for researchers and graduate students in the field of distributed coordination theory for robot teams, and for anyone interested in learning more about this rapidly growing field.

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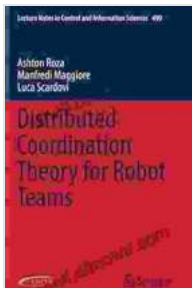
## **About the Author**

**Dr. Magnus Egerstedt** is a Professor in the School of Electrical and Computer Engineering at Georgia Institute of Technology. He is the author of over 100 papers in the field of distributed coordination theory for robot teams, and he is the recipient of several awards, including the IEEE Control Systems Society Outstanding Young Author Award.

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