

CONTENTS

HALAMAN PENGESAHAN	ii
PREFACE	iii
CONTENTS	vi
LIST OF FIGURES	viii
LIST OF TABLES	xi
Abstract	xii
<i>Intisari</i>	xiii
I INTRODUCTION	1
1.1 Motivation	1
1.2 Problem Statement	3
1.3 Thesis Organization	4
II SYSTEM MODELING	5
2.1 Sensor Coverage Modeling	5
2.2 Agent Modeling	9
2.3 Simulation Method	14
III COVERAGE CONTROL IN KNOWN FIELD	19
3.1 Voronoi-Based Strategy Optimization	19
3.1.1 Voronoi Tessellation	20
3.1.2 Voronoi Region Optimization	22

3.2	Voronoi-Based Controller	25
3.2.1	Lloyd-Max Algorithm	25
3.2.2	Distributed Lloyd-Max Algorithm	30
3.3	Mobile Robot Coverage Control	33
3.3.1	The Kinematic Controller	34
3.3.2	Obstacle and Collision Avoidance Strategy	38
3.4	Numerical Experiments	41
3.4.1	Performance against Network Topology	41
3.4.2	Coverage in Non-Uniform Interest Field	47
3.4.3	Coverage in Presence of Obstacles	51
IV	COVERAGE CONTROL IN UNKNOWN FIELD	58
4.1	Parameter Estimation	59
4.2	Distributed RLS	64
4.2.1	Consensus RLS	65
4.2.2	AMA RLS Implementation	68
4.3	Combining Coverage Control and Estimation	70
4.3.1	The Lloyd-Max and AMA-RLS Algorithm	70
4.3.2	Slight Modification to the AMA-RLS	71
4.4	Numerical Experiments	73
4.4.1	Lloyd-Max and Local RLS algorithm	74
4.4.2	Lloyd-Max and Original AMA-RLS Algorithm	78
4.4.3	Lloyd-Max and modified AMA-RLS algorithm	80
V	CONCLUSIONS	85
	REFERENCES	88