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network, that is, the mobile robots and the communication service connecting them. We then present the notion of control and communication law, and how a law is executed by a robotic network. These notions subsume the notions of synchronous network and distributed algorithm described in Section 1.4.

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physical location of as many robots as possible, i.e., to steer the robots to a common location. This objective is to be achieved with the limited information flow described in the model of the network. Typically, it will be impossible to solve the rendezvous problem for all robots if the robots are placed in such

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Coordination Algorithms. The intended audience of this book are first- and second-year graduate students in control and robotics from Computer Science, Electrical Engineering, Mechanical Engineering, and Aerospace Engineering. A familiarity with basic concepts from analysis, linear algebra, dynamical systems, and control theory is assumed.

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