

Adaptive finite time path-following control of underactuated surface vehicle with collision avoidance

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Journal of dynamic systems, measurement and control

2019; 141(12):e121008

ARTICLE IDENTIFIERS

DOI: 10.1115/1.4044272

PMID: unavailable

PMCID: not available

JOURNAL IDENTIFIERS

LCCN: 74644129 //r892

pISSN: 0022-0434

eISSN: 1528-9028

OCLC ID: 01585805

CONS ID: not available

US National Library of Medicine ID: 100971391

This article was identified from a query of the SafetyLit database.