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The overwhelming majority of a software system's lifespan is spent in use, not in design or implementation. So, why does conventional wisdom insist that software engineers focus primarily on the design and development of large-scale computing systems? In this collection of essays and articles, key members of Google's Site Reliability Team explain how and why their commitment to the entire lifecycle has enabled the company to successfully build, deploy, monitor, and maintain some of the largest software systems in the world. You'll learn the principles and practices that enable Google engineers to make systems more scalable, reliable, and efficient—lessons directly applicable to your organization. This book is divided into four sections: Introduction—Learn what site reliability engineering is and why it differs from conventional IT industry practices Principles—Examine the patterns, behaviors, and areas of concern that influence the work of a site reliability engineer (SRE) Practices—Understand the theory and practice of an SRE's day-to-day work: building and operating large distributed computing systems Management—Explore Google's best practices for training, communication, and meetings that your organization can use

This book examines mechatronics and automatic control systems. The book covers important emerging topics in signal processing, control theory, sensors, mechanic manufacturing systems and automation. The book presents papers from the 2013 International Conference on Mechatronics and Automatic Control Systems in Hangzhou, held in China during August 10-11, 2013.

Bipedal locomotion is among the most difficult challenges in control engineering. Most books treat the subject from a quasi-static perspective, overlooking the hybrid nature of bipedal mechanics. Feedback Control of Dynamic Bipedal Robot Locomotion is the first book to present a comprehensive and mathematically sound treatment of feedback design for achieving stable, agile, and efficient locomotion in bipedal robots.

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In this unique and groundbreaking treatise, expert authors lead you systematically through every step of the process, including: Mathematical modeling of walking and running gaits in planar robots Analysis of periodic orbits in hybrid systems Design and analysis of feedback systems for achieving stable periodic motions Algorithms for synthesizing feedback controllers Detailed simulation examples Experimental implementations on two bipedal test beds The elegance of the authors' approach is evident in the marriage of control theory and mechanics, uniting control-based presentation and mathematical custom with a mechanics-based approach to the problem and computational rendering. Concrete examples and numerous illustrations complement and clarify the mathematical discussion. A supporting Web site offers links to videos of several experiments along with MATLAB® code for several of the models. This one-of-a-kind book builds a solid understanding of the theoretical and practical aspects of truly dynamic locomotion in planar bipedal robots.

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