



COURSE DESCRIPTION CARD - SYLLABUS

Course name

Autonomous mobile robots

Course

Field of study

Automatic control and robotics

Area of study (specialization)

Robots and autonomous systems

Level of study

Second-cycle studies

Form of study

full-time

Year/Semester

1 / 2

Profile of study

general academic

Course offered in

Polish

Requirements

compulsory

Number of hours

Lecture

30

Laboratory classes

30

Other (e.g. online)

Tutorials

Projects/seminars

Number of credit points

Lecturers

Responsible for the course/lecturer:

dr hab. inż. Piotr Skrzypczyński

email: piotr.skrzypczynski@put.poznan.pl

tel. 061 6652198

Institute of Robotics and Machine Intelligence

ul. Piotrowo 3A 60-965 Poznań

Responsible for the course/lecturer:

Prerequisites

Student starting this course should have extended knowledge of programming practice, architecture of computer systems and operating systems, robotics and artificial intelligence. He should also have the ability to obtain information from the indicated sources.

Course objective

The aim of the course is to familiarize yourself with the issue of autonomous mobile robots and their applications in industry and services, and use the experience as a field for artificial intelligence methods.

Course-related learning outcomes

Knowledge



K2_W2 has structured and in-depth knowledge of artificial intelligence methods and their applications in automation and robotics systems;

, K2_W15 has knowledge of running a business, engineering project management and quality management;

, K2_W6 has detailed knowledge of the construction and use of advanced sensory systems;

Skills

K2_U12 can integrate and program specialized robotic systems;

K2_U25 will be able to construct an algorithm to solve a complex and unusual engineering task and a simple research problem, as well as implement, test and run it in a selected programming environment for selected operating systems;

K2_U26 is able to construct an algorithm for solving a complex measuring and computing-control task and implement, test and run it in a selected programming environment on a microprocessor platform;

Social competences

K2_K4 is aware of the need for a professional approach to technical issues, meticulous familiarization with the documentation and environmental conditions in which devices and their components can function;

Methods for verifying learning outcomes and assessment criteria

Learning outcomes presented above are verified as follows:

Lecture: written examination (theoretical knowledge test) in the field of lining issues]: concepts, methods, algorithms.

Laboratory: examining the practical skills of programming selected types of mobile robots and their components, carry out experiments, evaluate the reports.

Programme content

Lecture. Various issues associated with the construction, operation and use of autonomous vehicles. Construction and operation of mobile robots driving systems. Walking robots. Sensory systems. Architecture of mobile robots navigation systems. Basic issues of autonomous navigation (map building, localization, path planning). Applications of mobile robots. SLAM methods.

Laboratory. Simple wheeled robot control algorithms. The processing of information from external sensors. Build a model of the environment - examples. Implementation of the control reflex. Navigation issues - implementation of self-localization algorithms. SLAM algorithms, deep learning tools.

Teaching methods

. Lecture: multimedia presentation, illustrated with examples

2. Laboratory exercises: carrying out the tasks given by the teacher - practical exercises



Bibliography

Basic

11. S. Thrun, D. Fox, W. Burgard, Probabilistic Robotics, MIT Press, Cambridge, 2005
2. I. Nourbakhsh, R. Siegwart, D. Scaramuzza, Introduction to Autonomous Mobile Robots, MIT Press, Cambridge, 2011
3. P. Skrzypczyński, Metody analizy i redukcji niepewności percepcji w systemie nawigacji robota mobilnego, Wyd.PP, Poznań, 2007

Additional

1. R. Murphy, Introduction to AI Robotics, 2nd Edition, MIT Press, 2019
2. J. Borenstein, H. R. Everett, L. Feng, Where am I? Sensors and methods for mobile robot positioning, University of Michigan, 1996
3. A. Borkowski, R. Chojecki, M. Gnatowski, W. Mokrzycki, B. Siemiątkowska, J. Szklarski, Reprezentacja otoczenia robota mobilnego, EXIT, Warszawa, 2011.
4. J. Będkowski, Qualitative Spatio-Temporal Representation and Reasoning for Robotic Applications, EXIT. Warszawa, 2015

Breakdown of average student's workload

	Hours	ECTS
Total workload	125	4,0
Classes requiring direct contact with the teacher	65	2,0
Student's own work (literature studies, preparation for laboratory classes/tutorials, preparation for tests/exam, project preparation) ¹	60	2

¹ delete or add other activities as appropriate