



## COURSE DESCRIPTION CARD - SYLLABUS

Course name

Autonomous mobile robots [N2AiR1-RiSA>ARM]

### Course

Field of study

Automatic Control and Robotics

Year/Semester

1/2

Area of study (specialization)

Autonomous Robots and Systems

Profile of study

general academic

Level of study

second-cycle

Course offered in

polish

Form of study

part-time

Requirements

compulsory

### Number of hours

Lecture

20

Laboratory classes

20

Other (e.g. online)

0

Tutorials

0

Projects/seminars

0

### Number of credit points

4,00

### Coordinators

prof. dr hab. inż. Piotr Skrzypczyński  
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### Lecturers

### 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\_W25 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; K2\_U22 is able to critically evaluate and select appropriate methods and tools to solve of automation and robotics; is able to use innovative and unconventional tools unconventional tools in the field of automation and robotics;

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:

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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

33. S. Thrun, D. Fox, W. Burgard, Probabilistic Robotics, MIT Press, Cambridge, 3

53. I. Nourbakhsh, R. Siegwart, D. Scaramuzza, Introduction to Autonomous Mobile Robots, MIT Press, Cambridge, 3

333. P. Skrzypczyński, Metody analizy i redukcji niepewności percepcji w systemie nawigacji robota mobilnego, Wyd.PP, Poznań, 3

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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	100	4,00
Classes requiring direct contact with the teacher	40	1,50
Student's own work (literature studies, preparation for laboratory classes/ tutorials, preparation for tests/exam, project preparation)	60	2,50