



COURSE DESCRIPTION CARD - SYLLABUS

Course name

Basic tools and software for autonomous robots [S2AiR2-RiSA>PNiMPRA]

Course

Field of study

Automatic Control and Robotics

Year/Semester

1/1

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

full-time

Requirements

compulsory

Number of hours

Lecture

30

Laboratory classes

30

Other

0

Tutorials

0

Projects/seminars

0

Number of credit points

4,00

Coordinators

dr hab. inż. Dominik Belter prof. PP
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Lecturers

Prerequisites

A student starting this course should have basic knowledge of robotics and programming. He or she should also have the ability to obtain information from various sources and be ready to cooperate within the team.

Course objective

To provide students with knowledge about the tools used to program autonomous robots, the correct use of these tools and the integration of control systems.

Course-related learning outcomes

none

Methods for verifying learning outcomes and assessment criteria

Learning outcomes presented above are verified as follows:

The knowledge acquired during the lecture is verified by one 45-minute exam conducted in an examination session. The examination consists of 20-30 (test) questions and up to 5 open questions, differently scored. The credit threshold: 50% of points. Issues for the examination, on the basis of which the questions are

developed are made available during the lecture.

Skills acquired during the laboratory classes are verified on the basis of a credit colloquium consisting of 20 questions and checking the practical implementation of the traffic planning problem. The credit threshold: 50% of points.

Programme content

Lecture:

- 1 System scripts in bash/python, cron, bashrc, services
- Programming the Discovery chip from Linux
3. udev rules, fixed names for USB devices, low latency for USB communication
4. ROS node for communication in USB and publishing data
5. concurrent processing in C++ (threads, processes)
- 6 CUDA (performing operations on a graphic card)
- 7 Tensorflow + ROS (start up the network detecting objects in ROS)
- 8 Remote Master (ROS on multiple computers)
- 9 ArUco object detection for calibration
- 10 ROS bags (collection of data from camera for calibration)
- 11 TFs in ROS (reading transformations from previously saved ROS-bags)
- 12 Calibration of easyHandEye cameras (on ROS-bags)

Laboratory:

- 1 System scripts in bash/python, cron, bashrc, services
- Programming the Discovery chip from Linux
3. udev rules, fixed names for USB devices, low latency for USB communication
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- 6 CUDA (performing operations on a graphic card)
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Course topics

To provide students with knowledge about the tools used to program autonomous robots, the correct use of these tools and the integration of control systems.

Teaching methods

none

Bibliography

- Mark Mitchell, Jeffrey Oldham, Alex Samuel, Advanced Linux Programming, New Riders Publishing
- Robot Operating System (ROS), Springer 2016
- M. Galewski, STM32. Aplikacje i ćwiczenia w języku C, Wydawnictwo BTC, Legionowo 2011

Breakdown of average student's workload

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