

Modul: 5172080

Fundamentals of Mobile Robotics

Modulprofil

Prüfungsnummer

5172080

Dauer

1 Semester

Häufigkeit des Angebots

Jedes Wintersemester

SWS

4

ECTS-Credits (CP)

5.0

Workload

Angeleitete Studienzeit:

Präsenzzeit: 60 Std.

Selbststudienzeit: 90 Std.

Gesamt: 150 Std.

Lehrveranstaltungsart(en)

Seminaristischer Unterricht

Lehrsprache

Englisch

Organisation

Modulverantwortung

Prof. Dr.-Ing. Pascal Meißner

Dozierende

Prof. Dr.-Ing. Pascal Meißner

Verwendbarkeit

MAI

Studiensemester

2. Semester

Art des Moduls

Pflichtmodul

Verpflichtende Voraussetzungen gemäß SPO

None

Empfohlene Voraussetzungen

None

Inhalte

01. Introduction – Nomenclature, history, state of the art, module logistics
02. Linear Algebra and Probability Primer – Vectors and operations, matrices and operations, axioms of probability, independent events, Bayes rule
03. Bayes Filter – Recursive Bayesian updating, state transitions, Markov property, derivation
04. Probabilistic Modelling – Odometry- and velocity-based motion models, beam- and scan- based sensor models
05. Localization with Nonparametric Filters – Discrete Bayes filter, importance sampling, particle filter
06. Localization with Gaussian Filters – Kalman filter, Extended Kalman filter
07. Mapping with Known Poses – Occupancy maps, reflection probability maps
08. Landmark-based SLAM – SLAM problem, EKF SLAM, loop closing, Rao-Blackwellization, FastSLAM
09. Grid-based SLAM – Scan matching, FastSLAM, improved proposals, selective resampling
10. Motion and Path Planning – Configuration spaces, combinatorial planning, search algorithms, A* with extensions, collision avoidance
11. Markov Decision Processes – MDP definition, utility, value iteration, policy iteration

Prüfung

Verpflichtende Voraussetzung gemäß SPO für die Teilnahme an der Prüfung

Keine

Art der Prüfung

Sonstige Prüfung (soP) gemäß
§§ 26, 27 APO

Dauer/Form der Prüfung

Mündliche Prüfung

Die konkrete Festlegung der
abzuleistenden Prüfung erfolgt
im Studienplan

Prüfungssprache

Englisch

Voraussetzung für die Vergabe von Leistungspunkten

Keine

Lernergebnisse

- Apply the Bayes (filter) formula and sample from probability density functions
- Determine and apply probabilistic sensor and motion models
- Discuss the steps and components of realizations of Bayes filters
- Implement realizations of Bayes filters and compute location estimates for robots
- Build and analyze grid maps
- Differentiate between localization and SLAM systems as well as outline auxiliary techniques for SLAM solutions
- Assess and implement components of landmark- and grid-based solutions to the SLAM problem
- Differentiate between different path planning techniques and discuss the steps of collision avoidance solutions
- Apply and implement graph-search techniques for path planning
- Assess the Markov Decision Process definition as well as the concepts of Utility and Policy
- Apply dynamic programming on Markov Decision Problems to compute value functions and optimal policies

Literatur

- Probabilistic Robotics, Sebastian Thrun and Wolfram Burgard and Dieter Fox, MIT Press, 978-0262201629, 2005
- Artificial Intelligence: A Modern Approach, Stuart Russell and Peter Norvig, 4th ed. Prentice Hall, 978-0136042594, 2021