

<b>Module title</b>		<b>Abbreviation</b>
Robotics 2		10-I=RO2-122-m01
<b>Module coordinator</b>		<b>Module offered by</b>
holder of the Chair of Computer Science VII		Institute of Computer Science
<b>ECTS</b>	<b>Method of grading</b>	<b>Only after succ. compl. of module(s)</b>
8	numerical grade	--
<b>Duration</b>	<b>Module level</b>	<b>Other prerequisites</b>
1 semester	graduate	--
<b>Contents</b>		
<p>Foundations of dynamic systems, controllability and observability, controller design through pole assignment: feedback and feed-forward, state observer, feedback with state observer, time discrete systems, stochastic systems: foundations of stochastics, random processes, stochastic dynamic systems, Kalman filter: derivation, initialising, application examples, problems of Kalman filters, extended Kalman filter.</p>		
<b>Intended learning outcomes</b>		
<p>The students master all fundamentals that are necessary to understand Kalman filters and their use in applications of robotics. The students possess a knowledge of advanced controller and observer methods and recognise the connections between the dual pairs controllability - observability as well as controller design and observer design. They also recognise the relationship between the Kalman filter as a state estimator and an observer.</p>		
<b>Courses</b> (type, number of weekly contact hours, language – if other than German)		
V + T (no information on SWS (weekly contact hours) and course language available)		
<b>Method of assessment</b> (type, scope, language – if other than German, examination offered – if not every semester, information on whether module is creditable for bonus)		
written examination (approx. 60 to 90 minutes) Language of assessment: English		
<b>Allocation of places</b>		
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<b>Additional information</b>		
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<b>Referred to in LPO I</b> (examination regulations for teaching-degree programmes)		
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<b>Module appears in</b>		
Master's degree (1 major) Space Science and Technology (2012) Master's degree (1 major) Computer Science (2014)		