

PROJECT DESCRIPTION

1 Introduction

Mobile robotic platforms are becoming increasingly important in a variety of applications, including warehouse automation, medical assistance, cleaning services, agricultural robotics, and environmental monitoring, to cite a few.

1.1 Mobile robot control

Prototypical mobile robot tasks consist in visiting a sequence of locations in space. Once a path has been planned which passes through these locations, a controller has to be designed to make the robot follow this path. In this project we consider the problem of designing a controller to drive a ground mobile robot to a desired location.

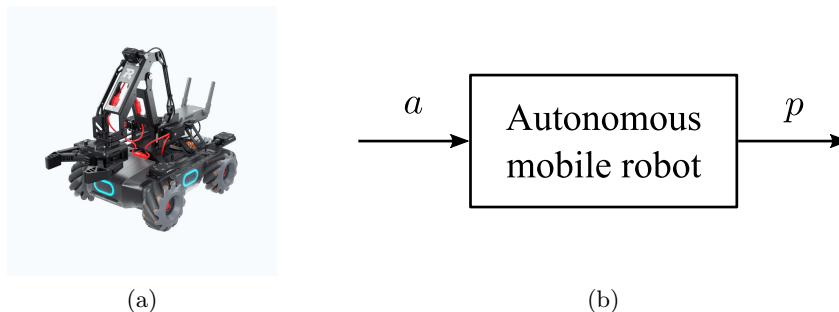


Figure 1: On the left: the DJI RoboMaster EP, a ground mobile robot on which your controller is going to be deployed and tested. On the right: a block diagram representation of the considered ground mobile robot. To control the robot we can send acceleration $a \in \mathbb{R}^2$ (input), and we have access to measurements of its position $p \in \mathbb{R}^2$ (output).

The block-diagram model of the considered mobile robotic system is given in Fig. 1. The control input to the system is the robot acceleration vector $u = [u_1, u_2]^T = [a_x, a_y]^T = a \in \mathbb{R}^2$, where a_x and a_y are the accelerations of the robot along the directions of the axes of the reference frame defined on the plane where the robot moves. The output of the system is the robot position vector $y = [y_1, y_2]^T = [p_x, p_y]^T = p \in \mathbb{R}^2$, where p_x and p_y are the components of the position of the robot along the axes of the reference frame. *Driving the robot to a desired fixed location corresponds to regulating the output of the system to a given constant reference value.*

The mathematical model of the system is not known but it is possible to probe the system by supplying an acceleration input signal and measuring the corresponding position output signal. This way, one can build a mathematical model of the system to be used to design a controller that fulfills the desired specifications.

1.2 Code

The code provided in the file `system_model.py` contains the Python class `SystemModel` that implements the dynamics of the mobile robot. This class allows us to faithfully simulate the motion of the robot and obtain the output response to a given input signal. The latter can be done by calling the class method `sim` as follows:

```
output_signal = sm.sim(input_signal),
```

where `sm` is an object of the class `SystemModel`, and `input_signal` and `output_signal` are the input and output signals, respectively, represented as `numpy` arrays whose shape is $(L, 2)$. The variable L is the length of the signal measured in number of time steps, where one time step lasts $\Delta t = 0.001$ s. This way, if a signal lasts for 1s, the length of the `numpy` array representing the signal will be 1000.

The class `SystemModel` has one another method, `step`, which can be used as follows to obtain the measured output vector \bar{y} at time $t + \Delta t$ in response to an input signal $u(\tau) = \bar{u}, \forall \tau \in [t, t + \Delta t]$:

```
y_bar = sm.step(u_bar),
```

where `u_bar` and `y_bar` are the input and measured output vectors, represented as `numpy` arrays whose shape is $(2,)$.

2 Project tasks

Task 1 consists of collecting and processing input-output data of the robot to control, which will be used in Task 2 to build a mathematical model of the robot, which, in turn, will be used in Task 3 to design a controller for the robot.

2.1 Task 1

Complete the items described below:

- **Item 1 (2 points)** Define constant input signals u_1, u_2 of amplitude 1 over a time horizon of 15s. Generate the corresponding output signals y_1, y_2 .
- **Item 2 (2 points)** Plot the signals u_1, u_2, y_1, y_2 .
- **Item 3 (3 points)** Design a third order low-pass filter with real and coincident poles and cut-off frequency $\omega_c = 10$ rad/s.
- **Item 4 (3 points)** Filter the signals y_1, y_2 using the designed low-pass filter. Plot the filtered signals.

3 Deliverables and grading

The deliverables for each task consist of:

- A report, in PDF format, written using the L^AT_EX or Microsoft Word IEEE conference proceedings template available [here](#), of maximum 2 pages, with default font size and margins, reporting the required plots and explaining the approach
- A Python script (`.py` file) containing the code to solve the task

Important notes

- If the format of a project task submission is not as above, the project task will not be graded.
- The report should contain the explanation of the steps followed to solve each item of a project task, as well as the reference to the part of the code that solves each item, otherwise the corresponding item will not be graded.

4 Logistic details

- The project work is carried out in groups of 2 students. Groups of one are permitted only if an odd number of students are enrolled. Project groups are formed on LEARN.
- Project submissions, one per group, will be handled via LEARN.
- Multiple submissions will be accepted via LEARN before the deadline, but only the most recent one will be available for grading.