Course guides
220072 - 220072 - Advanced Control Systems

Unit in charge: Terrassa School of Industrial, Aerospace and Audiovisual Engineering
Teaching unit: 707 - ESAII - Department of Automatic Control.

Degree:
BACHELOR’S DEGREE IN ELECTRICAL ENGINEERING (Syllabus 2009). (Optional subject).
BACHELOR’S DEGREE IN INDUSTRIAL ELECTRONICS AND AUTOMATIC CONTROL ENGINEERING (Syllabus 2009). (Optional subject).
BACHELOR’S DEGREE IN AEROSPACE TECHNOLOGY ENGINEERING (Syllabus 2010). (Optional subject).
BACHELOR’S DEGREE IN AEROSPACE VEHICLE ENGINEERING (Syllabus 2010). (Optional subject).
BACHELOR’S DEGREE IN INDUSTRIAL TECHNOLOGY ENGINEERING (Syllabus 2010). (Optional subject).

Academic year: 2021 ECTS Credits: 3.0 Languages: English

LECTURER
Coordinating lecturer: Masip Alvarez, Albert
Others: Cayero Becerra, Julián Francisco

PRIOR SKILLS
This course requires the student to have basic skills in:
Modelling of dynamic systems and transfer function
Control techniques (PID tuning)

TEACHING METHODOLOGY
The course is divided into parts:
Theory classes
Laboratory sessions
Self-study for doing exercises and activities.
In the theory classes, teachers will introduce the theoretical basis of the concepts, methods and results and illustrate them with examples appropriate to facilitate their understanding.
In the lab sessions, teachers guide students in applying theoretical concepts to solve problems, always using critical reasoning. We propose that students solve two autonomous robot control projects in and outside the classroom, to promote contact and use the basic tools needed to solve problems.
Students, independently, need to work on the materials provided by teachers in order to fix and assimilate the concepts.
The teachers provide the syllabus and monitoring of activities (by ATENEA).

LEARNING OBJECTIVES OF THE SUBJECT
This course is about autonomous mobile robots as seen from the control point of view. The main types of mobile robots (ground, aerial and underwater) are reviewed and their common control architecture is presented. This architecture introduces four control problem categories which are examined (planning, navigation, perception and control). The course is about the control problems and the control tools to solve some of them.
One of the main objectives of the course is to acquire a hands-on experience, which will be obtained through the robotic control projects.
The principal tools of advanced control system design are introduced in the theory lectures and applied in the lab. These tools are the operational aspects of discrete control theory and the state space representation and analysis framework, which allows the natural introduction of advanced control techniques, such as optimal control, model predictive control, etc.
**STUDY LOAD**

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<tr>
<th>Type</th>
<th>Hours</th>
<th>Percentage</th>
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<tr>
<td>Self study</td>
<td>45,0</td>
<td>60.00</td>
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<tr>
<td>Hours large group</td>
<td>30,0</td>
<td>40.00</td>
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**Total learning time:** 75 h

**CONTENTS**

**Module 1: Basics for Drone manoeuvring**

**Description:**
Drone flight principles
AR-Drone architecture (soft+hard) Matlab,coms,fisica
ROS basics/fundamentals
AR-Drone simulation model

**Specific objectives:**

**Related activities:**
1, 2, 3

**Full-or-part-time:** 25h
- Theory classes: 10h
- Self study: 15h

**Module 2: Identification and controller design**

**Description:**
Models for control: transfer functions
Identification of transfer functions from experimental data
Controller design based on pole placement using transfer functions
Cascade control structure

**Related activities:**
1, 2, 3

**Full-or-part-time:** 25h
- Theory classes: 10h
- Self study: 15h

**Mission control**

**Description:**
Image processing
Path tracking algorithm
State machines

**Related activities:**
1, 2, 3

**Full-or-part-time:** 25h
- Theory classes: 10h
- Self study: 15h
## ACTIVITIES

<table>
<thead>
<tr>
<th>1. Theory lectures</th>
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<tr>
<td><strong>Description:</strong> Exposition of the subject theory contents.</td>
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<tr>
<td><strong>Specific objectives:</strong> Knowledge transfer, creation of a conceptual reference frame, solving questions and generating interest about the subject.</td>
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<td><strong>Material:</strong> Slide compilations and handouts at Atenea General bibliography of the subject</td>
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<td><strong>Full-or-part-time:</strong> 10h Theory classes: 10h</td>
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<th>2. Laboratory projects</th>
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<tr>
<td><strong>Description:</strong> Students, in groups, follow the instructions to resolve a practical control problem. These sessions take place at the lab and there are two problems to solve. Terrestrial and aerial mobile robots are the platforms used in the projects developed in the lab sessions.</td>
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<tr>
<td><strong>Specific objectives:</strong> Proper application of control design methodology.</td>
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<tr>
<td><strong>Material:</strong> Project instructions at Atenea Simulation software (Matlab) Lab plants (aerial and mobile robots) Course handouts and notes</td>
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<td><strong>Delivery:</strong> Each group has to deliver a report describing the results of the projects, the methodology and techniques applied to obtain the final results. A practical demonstrations is also required.</td>
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<td><strong>Full-or-part-time:</strong> 53h Theory classes: 18h Self study: 35h</td>
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3. Final examination

Description:
Written individual examination about the concepts of theory modules. The examination includes conceptual questions, test questions, and problems to be solved by hand.

Specific objectives:
Assess the knowledge acquisition of activities 1, 2. Distinguish from the group evaluation in activity 2.

Material:
Examination instructions.

Delivery:
Answers to the questions and solutions to the problems posed in the instructions.

Full-or-part-time: 12h
Theory classes: 2h
Self study: 10h

GRADING SYSTEM

Individual exam: 40%
Lab deliverings: 60%
The students who do not pass the subject can take an additional global written exam that will take place the date stated in the calendar of final exams. The grade obtained in this exam will replace the one of the final exam in case it is higher. The maximum final mark in this case will be 5.0

BIBLIOGRAPHY

Basic: