

# CMSC 498E: Robotics

Fall 2023

Tu, Th: 2:00pm – 3:15pm

CSI 2117

## Instructor:

Dinesh Manocha ([dmanocha@umd.edu](mailto:dmanocha@umd.edu))

## Prerequisites:

Minimum grade of C- or higher in CMSC330 and CMSC351, 1 course with a minimum grade of C- or higher from (MATH240, MATH341, MATH461).

## Course Objective

To learn about the design, programming, and control of robotic systems.

## Approach:

Class lectures, mathematical homeworks, programming assignments, class project.

## Syllabus:

Topics include kinematics, inverse kinematics, dynamics, actuation, sensing, manipulation, control, motion planning, multi-agent navigation. Applications including industrial and mobile robots, and autonomous driving

**Course Background:** Robotics is the study of robot design, programming, and control. Typically, a robot is referred to as an agent that can be programmed to perform a variety of tasks -- both with and without human intervention. A robot is often manifested and realized by mechanical and electrical components to carry out its actions in the physical world. Robots frequently receive input from noisy sensors, consider geometric and mechanical constraints, and operate in the physical world through imprecise actuators. The design and analysis of robot algorithms and computational elements, therefore, raises a unique combination of questions in computational and differential geometry, algorithm design, control theory, mechanics, computer science, and system engineering.

In this course, we will give an overview on fundamental components of robotic systems, including the sensing and actuation, control and modeling of motion and perception, dynamics and kinematics, motion planning and manipulation of robots. Students will learn about implementation of basic simulation programs that produce interesting results and verify its correctness. The goal of this class is to get students an appreciation of computational methods and engineering issues for modeling robots. We will discuss various considerations and tradeoffs used in designing various methodologies (e.g., time, space, robustness, and generality). This will include data structures, algorithms, computational methods, simulation

techniques, runtime complexity, system implementation and integration, in the context of multi-disciplinary design.

### **Course Outline:**

*Numbers in parentheses indicate approximate number of weeks*

- Definition and history of robotics (1)
- Kinematics (1)
- Inverse kinematics (1)
- Dynamics (1)
- Actuation/Control (1)
- Sensing (1)
- Manipulation (1)
- Collision Detection (1)
- Motion Planning (2)
- Multi-agent/Multi-robot systems (2)
- Applications (2)

### **Grading Scheme:**

1. Homework assignments (40%)
2. Class Participation and Quizzes: 10%
3. Mid Term: 20%
4. Final Exam or Course Project: 30%

### **Homework Assignments:**

*7 assignments (estimated): Problem Sets and Programming Assignments*