



AAE1001 Introduction to Artificial Intelligence and Data Analytics in Aerospace and Aviation Engineering

Week 11 (Assessments Guideline)

Dr Guohao Zhang, assisted by

Dr Penghui XU, Mr Zekun ZHANG, Mr Di HAI, Mr Yidi CHEN, Mr Zhen LYU



Necessary Information

- Course Repository (project download) link:

[https://github.com/IPNL-POLYU/PolyU AAE1001 Github Project](https://github.com/IPNL-POLYU/PolyU_AAE1001_Github_Project)

- TA Information & Contact:

Group 1-3: Dr Penghui XU - xphsean12@163.com

Group 4-6: Mr Zekun ZHANG - zekun.zhang@connect.polyu.hk

Group 7-8: Mr Di HAI - 23037537R@connect.polyu.hk

Group 9-10: Mr Yidi CHEN - yi-di.chen@connect.polyu.hk

Group 11-12: Mr Zhen LYU - zhenn.lyu@connect.polyu.hk



Assessment

- **Laboratory (35%)**
 - **GitHub Repository (25%):**
Group project contents (codes, results, etc.)
Report (Readme file per group)
Reflective essay (Individual)
 - **Peer Assessment Form (10%)**
- **Group Project Presentation (25%)**
(both group and individual performances are considered)



Group project contents



The screenshot shows a GitHub repository page. At the top, the repository name 'AAE1001_group_6' is highlighted with a red box. Below it, the repository content is listed, also highlighted with a red box. The content includes files like 'Group 6 Task 1.py', 'Group 6 Task 2.py', and 'Group 6 Task 3(increase by 1).ggb'. A large red arrow points from the repository name to the text 'Repository name format:'. Another red arrow points from the repository content to the text 'Repository content:'. A third red arrow points from the bottom-left section to the text 'Repository Readme file as the project report'.

Code Issues Pull requests Actions Projects Security Insights Settings

AAE1001_group_6 Private

main 6 Branches 0 Tags Go to file + Code

AndyDeng336462 Rename Grp 6 Task A2 without diagonal... 5e8b43f · last year 148 Commits

Group 6 Task 1.py Update Group 6 Task 1.py last year

Group 6 Task 2.py alert the color of cost saving area last year

Group 6 Task 3(increase by 1).ggb Rename Group 6 task 3(increase by 1).g... last year

Group 6 Task 3(increase by 1).pdf Rename Group 6 Task 2(increase by 1).p... last year

Group 6 Task 3(increase by 50).py Add files via upload last year

Group 6 Task A1 .py A1(2 checkpoints) last year

Group 6 Task A2 with diagonal r... Rename Grp 6 Task A2 with diagonal re... last year

Group 6 Task A2 without diagon... Rename Grp 6 Task A2 without diagona... last year

Group 6 Task A3--Breadth-First S... similar graph, different core last year

Group 6 Task A3--Dijkstra's Algo... similar graph, different core last year

README.md Update README.md last year

a_star_original.py update route last year

README

Group member

DENG Jiabao (Group Leader)

WANG Qiushi

About

No description, website, or topics provided.

Readme Activity 0 stars 1 watching 0 forks

Releases

No releases published Create a new release

Packages

No packages published Publish your first package

Contributors 6

Languages

Python 100.0%

Suggested workflows

Based on your tech stack

Python application Configure

Create and test a Python application.

Repository name format:
AAE1001_25_Group_[number]

Repository content:
Collection important documents related to the project. (create separate code file for each task)

Repository Readme file as the project report



Readme in GitHub Repository

What is a README.md?

A file for your repository front page

Contains:

- Information about your repository
- Directory
- Contribution
- And more...

Important? ... Yes!



README.md

UrbanNav

An Open-Sourcing Localization Dataset Collected in Asian Urban Canyons, including Tokyo and Hong Kong

This repository is the usage page of the [UrbanNav dataset](#). Positioning and localization in deep urban canyons using low-cost sensors is still a challenging problem. The accuracy of GNSS can be severely challenged in urban canyons due to the high-rising buildings, leading to numerous Non-line-of-sight (NLOS) receptions and multipath effects. Moreover, the excessive dynamic objects can also distort the performance of LiDAR, and camera. The UrbanNav dataset wishes to provide a challenging data source to the community to further accelerate the study of accurate and robust positioning in challenging urban canyons. The dataset includes sensor measurements from GNSS receiver, LiDAR, camera and IMU, together with accurate ground truth from SPAN-CPT system. Different from the existing dataset, such as [Waymo](#), [KITTI](#), UrbanNav provide raw GNSS RINEX data. In this case, users can improve the performance of GNSS positioning via raw data. In short, the [UrbanNav dataset](#) pose a special focus on improving GNSS positioning in urban canyons, but also provide sensor measurements from LiDAR, camera and IMU. If you got any problems when using the dataset and cannot find a satisfactory solution in the issue list, please open a new issue and we will reply ASAP.

Key words: Positioning, Localization, GNSS Positioning, Urban Canyons, GNSS Raw Data, Dynamic Objects, GNSS/INS/LiDAR/Camera, Ground Truth



Hong Kong Dataset

Hong Kong Team lead by:
Prof Wu Chen, Hong Kong Polytechnic University, Hong Kong.
Dr. Zhizhao Liu, Hong Kong Polytechnic University, Hong Kong.
Dr. Li-Ta Hsu, Hong Kong Polytechnic University, Hong Kong.



Tokyo Dataset

Tokyo Team lead by:
Prof Nobuski Kubo, Tokyo University of Marine Science and Technology, Japan
Prof Junichi Meguro, Meijo University, Japan
Dr. Taro Suzuki, Chiba Institute of Technology, Japan

Important Notes:

- **About access to GNSS RINEX file:** The GNSS measurements is provided as GNSS RINEX data. We will recently open-source a package, the [GraphGNSSLib](#), which provide easy access to the GNSS RINEX file and publish the data as customized ROS message. Meanwhile, we [GraphGNSSLib](#) also provide the capabilities of GNSS positioning and real-time kinematic (RTK) using factor graph optimization (FGO). If you wish to use the GraphGNSSLib, keep an eye on the update of this repo.
- **Dataset contribution:** Researchers who wish to contribute their dataset as part of the UrbanNav dataset, please feel free to contact us via email darren-f.huang@connect.polyu.hk, welson.wen@polyu.edu.hk, and lt.hsu@polyu.edu.hk. We wish the UrbanNav can be a platform for navigation solution development, validation and sharing.
- **Algorithm validation and contribution:** Researchers are welcomed to share their navigation solution results, source code to the UrbanNav dataset after a code review process, e.g. code for GNSS/INS integration or LiDAR SLAM, etc.

Overview

- Objective
- Hong Kong Dataset
- Tokyo Dataset
- Getting Started
- Acknowledgements
- License
- Related Publications

成就未來

7



Source Code vs Preview of README.md

Source Code

```
1 <!-- TABLE OF CONTENTS -->
2 <details open="open">
3   <summary><h2 style="display: inline-block">Table of Contents</h2></summary>
4   <li><a href="#Background-of-Path-Planning-to-Aviation-Engineering">Background of Path Planning to Aviation Engineering</a></li>
5   <li><a href="#Theory-of-Path-Planning-Algorithm">Theory of Path Planning Algorithm</a></li>
6   <li><a href="#Introduction-of-the-Engineering-Tools ">Introduction of the Engineering Tools </a></li>
7   </ol>
8 </details>
9
10
11
12 <!-- ABOUT THE PROJECT -->
13 # Background of Path Planning to Aviation Engineering
14
15 "Lorem ipsum dolor sit amet, consectetur adipiscing elit, sed do eiusmod tempor incididunt ut labore et dolore magna aliqua. Ut enim ad minim veniam, quis nostrud exercitation ullamco laboris nisi ut aliquip ex ea commodo consequat. Duis aute irure dolor in reprehenderit in voluptate velit esse cillum dolore eu fugiat nulla pariatur. Excepteur sint occaecat cupidatat non proident, sunt in culpa qui officia deserunt mollit anim id est laborum."
16
17 ![[This is an image]](https://www.researchgate.net/profile/Jan-Bieser/publication/333867743/figure/fig2/AS:771428257374208@1560934237674/Bar-chart-showing-the-number-of-observations-value-attribute-for-each-age-group-key.png)
18
19 "At vero eos et accusamus et iusto odio dignissimos ducimus qui blanditiis praesentium voluptatum deleniti atque corrupti quos dolores et quas molestias excepturi sint occaecati cupiditate non provident, similiq[ue] sunt in culpa qui officia deserunt mollitia animi, id est laborum et dolorum fuga. Et harum quidem rerum facilis est et expedita distinctio. Nam libero tempore, cum soluta nobis est eligendi optio cumque nihil impedit quo minus id quod maxime placeat facere possimus, omnis voluptas assumenda est, omnis dolor repellendus. Temporibus autem quibusdam et aut officiis debitis aut rerum necessitatibus saepe eveniet ut et voluptates repudiandae sint et molestiae non recusandae. Itaque earum rerum hic tenetur a sapiente delectus, ut aut reiciendis voluptatibus maiores alias consequatur aut perferendis doloribus asperiores repellat."
20
21 "On the other hand, we denounce with righteous indignation and dislike men who are so beguiled and demoralized by the charms of pleasure of the moment, so blinded by desire, that they cannot foresee the pain and trouble that are bound to ensue; and equal blame belongs to those who fail in their duty through weakness of will, which is the same as saying through shrinking from toil and pain. These cases are perfectly simple and easy to distinguish. In a free hour, when our power of choice is untrammelled and when nothing prevents our being able to do what we like best, every pleasure is to be welcomed and every pain avoided. But in certain circumstances and owing to the claims of duty or the obligations of business it will frequently occur that pleasures have to be repudiated and annoyances accepted. The wise man therefore always holds in these matters to this principle of selection: he rejects pleasures to secure other greater pleasures, or else he endures pains to avoid worse pains."
22
```

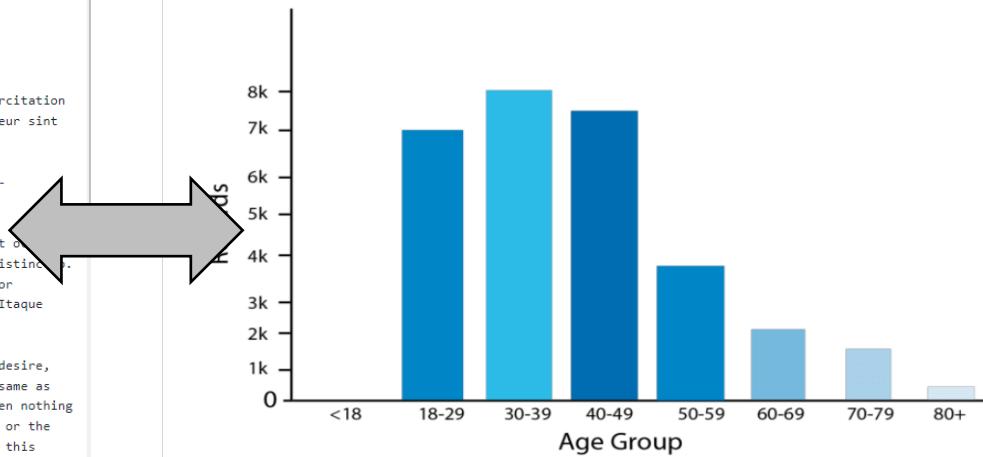
Preview

Table of Contents

- [Background of Path Planning to Aviation Engineering](#Background-of-Path-Planning-to-Aviation-Engineering)
- [Theory of Path Planning Algorithm](#Theory-of-Path-Planning-Algorithm)
- [Introduction of the Engineering Tools](#Introduction-of-the-Engineering-Tools)

Background of Path Planning to Aviation Engineering

"Lorem ipsum dolor sit amet, consectetur adipiscing elit, sed do eiusmod tempor incididunt ut labore et dolore magna aliqua. Ut enim ad minim veniam, quis nostrud exercitation ullamco laboris nisi ut aliquip ex ea commodo consequat. Duis aute irure dolor in reprehenderit in voluptate velit esse cillum dolore eu fugiat nulla pariatur. Excepteur sint occaecat cupidatat non proident, sunt in culpa qui officia deserunt mollit anim id est laborum."



"At vero eos et accusamus et iusto odio dignissimos ducimus qui blanditiis praesentium voluptatum deleniti atque corrupti quos dolores et quas molestias excepturi sint occaecati cupiditate non provident, similiq[ue] sunt in culpa qui officia deserunt mollitia animi, id est laborum et dolorum fuga. Et harum quidem rerum facilis est et expedita distinctio. Nam libero tempore, cum soluta nobis est eligendi optio cumque nihil impedit quo minus id quod maxime placeat facere possimus, omnis voluptas assumenda est, omnis dolor repellendus. Temporibus autem quibusdam et aut officiis debitis aut rerum necessitatibus saepe eveniet ut et voluptates repudiandae sint et molestiae non recusandae. Itaque earum rerum hic tenetur a sapiente delectus, ut aut reiciendis voluptatibus maiores alias consequatur aut perferendis doloribus asperiores repellat."



How to Create a README.md?

 **Public**
Anyone on the internet can see this repository. You choose who can commit.

 **Private**
You choose who can see and commit to this repository.

Initialize this repository with:

Skip this step if you're importing an existing repository.

Add a README file
This is where you can write a long description for your project. [Learn more.](#)

Add .gitignore
Choose which files not to track from a list of templates. [Learn more.](#)

Choose a license
A license tells others what they can and can't do with your code. [Learn more.](#)

Quick setup — if you've done this kind of thing before

[Set up in Desktop](#) or [HTTPS](#) [SSH](#) <https://github.com/melvincheng0830/xd.git>

Get started by [creating a new file](#) or [uploading an existing file](#). We recommend every repository includes **README**, **LICENSE**, and **.gitignore**.

...or create a new repository on the command line

```
echo "# xd" >> README.md
git init
git add README.md
git commit -m "first commit"
git branch -M main
git remote add origin https://github.com/melvincheng0830/xd.git
git push -u origin main
```



Basic Features of README.md?

1. Basic text, titles and subtitles
2. Table of contents
3. Inserting figures / photos





Basic Text, Titles and Subtitles

- To create normal texts, simply type them in to the source code
- To create a main title, add a '#' at the beginning
 - *# This is the Main Title*
 - *##### More # makes smaller titles*

Background of Path Planning to Aviation Engineering

Smaller Title

Even smaller title

```
# Background of Path Planning to Aviation Engineering
### Smaller Title
##### Even smaller title
```



Table of Contents

- You need to have titles before creating a table of Contents
- Format of a table of contents
- Everything like fonts, text sizes and more can be altered!

```
<!-- TABLE OF CONTENTS -->
<details open="open">
  <summary><h2 style="display: inline-block">Table of Contents</h2></summary>
  <ol>
    <li><a href="#Background-of-Path-Planning-to-Aviation-Engineering">Background of Path Planning to Aviation Engineering</a></li>
    <li><a href="#Theory-of-Path-Planning-Algorithm">Theory of Path Planning Algorithm</a></li>
    <li><a href="#Introduction-of-the-Engineering-Tools ">Introduction of the Engineering Tools </a></li>
  </ol>
</details>
```

Text to be shown

Titles to be directed to



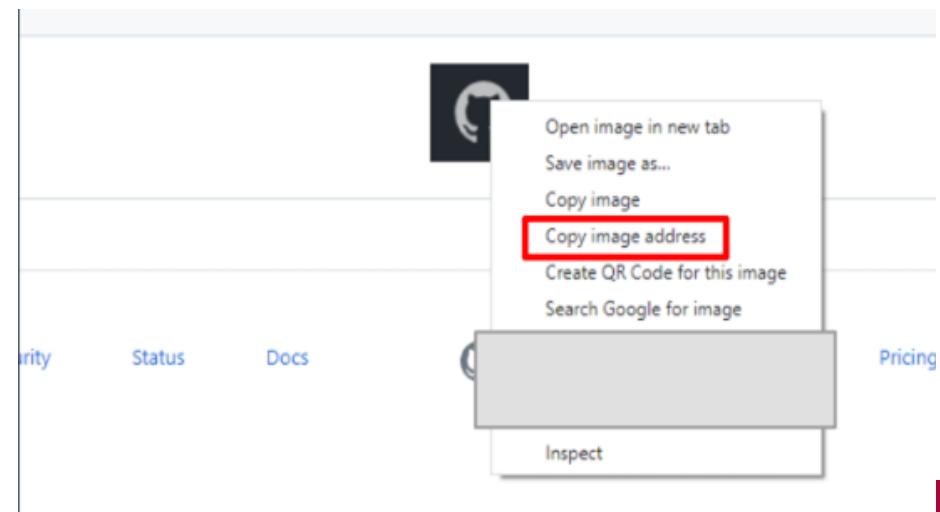
Inserting Figures / Photos

- You need to provide a link of the photo for this to work
- For screenshots you make, you can upload them to your repository and do the same thing by copying the image address!
- Example:

![This is an image](<https://www.researchgate.net/profile/Jan-Bieser/publication/333867743/figure/fig2/AS:771428257374208@1560934237674/Bar-chart-showing-the-number-of-observations-value-attribute-for-each-age-group-key.png>)

Message shown when picture cannot load

You can get the link for a photo by right clicking on it and select 'Copy link address'





Example

```

1 <!-- TABLE OF CONTENTS -->
2 <details open="open">
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15 "Lorem ipsum dolor sit amet, consectetur adipiscing elit, sed do eiusmod tempor incididunt ut labore et dolore magna aliqua. Ut enim ad minim veniam, quis nostrud exercitation ullamco laboris nisi ut aliquip ex ea commodo consequat. Duis aute irure dolor in reprehenderit in voluptate velit esse cillum dolore eu fugiat nulla pariatur. Excepteur sint occaecat cupidatat non proident, sunt in culpa qui officia deserunt mollit anim id est laborum."
16
17 ![[This is an image](https://www.researchgate.net/profile/Jan-Bieser/publication/333867743/figure/fig2/AS:771428257374208@1560934237674/Bar-chart-showing-the-number-of-observations-value-attribute-for-each-age-group-key.png)
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19 "At vero eos et accusamus et iusto odio dignissimos ducimus qui blanditiis praesentium voluptatum deleniti atque corrupti quos dolores et quas molestias excepturi sint occaecati cupiditate non provident, similiqute sunt in culpa qui officia deserunt mollitia animi, id est laborum et dolorum fuga. Et harum quidem rerum facilis est et expedita distinctio. Nam libero tempore, cum soluta nobis est eligendi optio cumque nihil impedit quo minus id quod maxime placeat facere possimus, omnis voluptas assumenda est, omnis dolor repellendus. Temporibus autem quibusdam et aut officiis debitis aut rerum necessitatibus saepe eveniet ut et voluptates repudiandae sint et molestiae non recusandae. Itaque earum rerum hic tenetur a sapiente delectus, ut aut reiciendis voluptatibus maiores alias consequatur aut perferendis doloribus asperiores repellat."
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21 "On the other hand, we denounce with righteous indignation and dislike men who are so beguiled and demoralized by the charms of pleasure of the moment, so blinded by desire, that they cannot foresee the pain and trouble that are bound to ensue; and equal blame belongs to those who fail in their duty through weakness of will, which is the same as saying through shrinking from toil and pain. These cases are perfectly simple and easy to distinguish. In a free hour, when our power of choice is untrammelled and when nothing prevents our being able to do what we like best, every pleasure is to be welcomed and every pain avoided. But in certain circumstances and owing to the claims of duty or the obligations of business it will frequently occur that pleasures have to be repudiated and annoyances accepted. The wise man therefore always holds in these matters to this principle of selection: he rejects pleasures to secure other greater pleasures, or else he endures pains to avoid worse pains."
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```

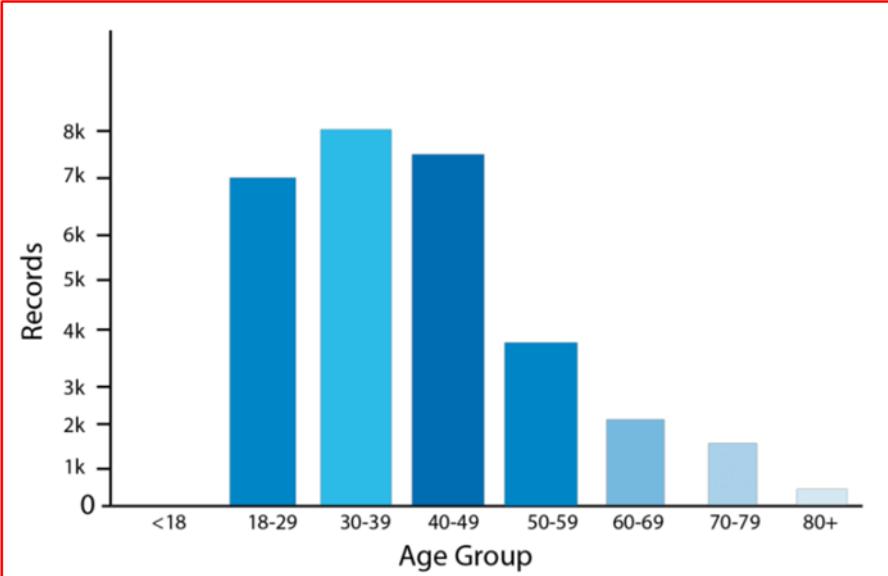
- Just like writing an HTML page
- Different formatting syntax creates corresponding visual formatting for the README page

Table of Contents

- Background of Path Planning to Aviation Engineering
- Theory of Path Planning Algorithm
- Introduction of the Engineering Tools

Background of Path Planning to Aviation Engineering

"Lorem ipsum dolor sit amet, consectetur adipiscing elit, sed do eiusmod tempor incididunt ut labore et dolore magna aliqua. Ut enim ad minim veniam, quis nostrud exercitation ullamco laboris nisi ut aliquip ex ea commodo consequat. Duis aute irure dolor in reprehenderit in voluptate velit esse cillum dolore eu fugiat nulla pariatur. Excepteur sint occaecat cupidatat non proident, sunt in culpa qui officia deserunt mollit anim id est laborum."

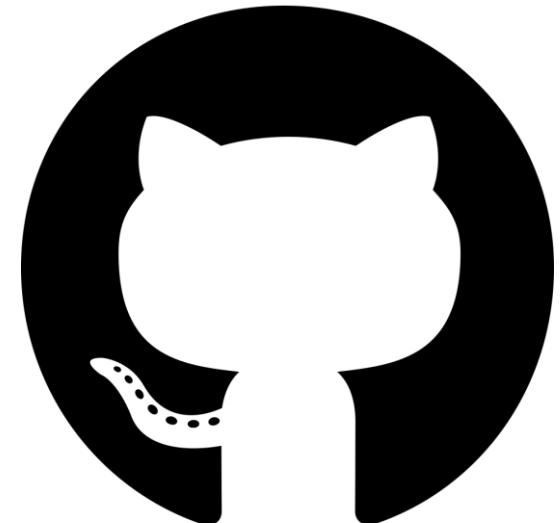


"At vero eos et accusamus et iusto odio dignissimos ducimus qui blanditiis praesentium voluptatum deleniti atque corrupti quos dolores et quas molestias excepturi sint occaecati cupiditate non provident, similiqute sunt in culpa qui officia deserunt mollitia animi, id est laborum et dolorum fuga. Et harum quidem rerum facilis est et expedita distinctio. Nam libero tempore, cum soluta nobis est eligendi optio cumque nihil impedit quo minus id quod maxime placeat facere possimus, omnis voluptas assumenda est, omnis dolor repellendus. Temporibus autem quibusdam et aut officiis debitis aut rerum necessitatibus saepe eveniet ut et voluptates repudiandae sint et molestiae non recusandae. Itaque earum rerum hic tenetur a sapiente delectus, ut aut reiciendis voluptatibus maiores alias consequatur aut perferendis doloribus asperiores repellat."



Your README.md Report

- You are required to include the basic features mentioned in this PPT
 - Table of content, image, titling
 - **One report per group, with individual reflective essay at the end (200-250 words)**
- For bonus marks:
 - Search for more features on the web and include them appropriately to your README file!
 - What to add?
 - A gif showing your path planning plot
 - Other potential materials you find useful
- Useful links:
 - GitHub official tutorial





Peer Assessment



AAE1001 Introduction to Artificial Intelligence and Data Analytics in Aerospace and Aviation Engineering

Confidential Peer Assessment Form

You are required to assess your peers' and your own contribution for key tasks of the project (given in the table). The contribution rating varies from 0% to 100%. 0% means no contribution at all, while 100% means all the work are carried out by the student concerned. The information provided will be treated with **strict confidentiality** and will not be revealed to any of your classmates.

Group No. _____

Project Tasks	Distribution of contribution (total 100% for each item)					
	Name of Assessor: (Your name)	Name of your group mate:	Total			
Example:	40%	20%	10%	10%	20%	100%
Task 1: Discussion on the idea to solve path planning tasks						100%
Task 2: Path-planning python coding						100%
Task 3: GitHub participation						100%
Task 4: Project report writing						100%
Task 5: Project presentation						

Comments:



Project Presentation



Project Presentation

- Face2F presentation by groups
 - Around 15 minutes in total
 - **Everyone** has roughly **2** minutes to present
 - **Must have a slide**
 - Inform the **presenter sequence** to the lecturer or TA after your presentation

Generating the map: Obstacles

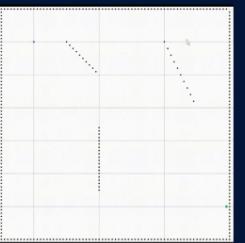
```
Variable obstacle density
for i in range(int(obstacle_density * 60 * 60)):
    ox_temp = random.randint(-9, 59)
    oy_temp = random.randint(-9, 59)
    if math.sqrt((ox_temp - sx)**2 + (oy_temp - sy)**2) < obstacle_clearance or math.sqrt((ox_temp - gx)**2 + (oy_temp - gy)**2) <
        continue
    ox.append(ox_temp)
    oy.append(oy_temp)

Stores coordinates if
proximity check passed
```

Proximity check for start/end points

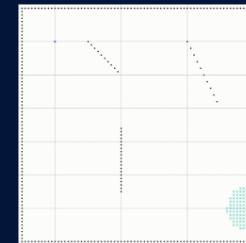
(GPT-4o, 06 Aug. version, GenAI)

Theories of different algorithms



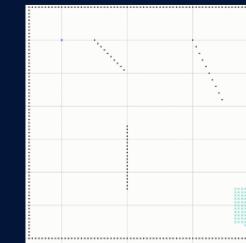
A*

- F: Total estimated cost of a path
- G: Distance traveled so far.
- H: Estimated distance to the goal (heuristic).
- Calculates $F = G + H$ and always chooses the path with the lowest F.



Dijkstra

- Picks the closest unvisited point and updates neighbors.
- Repeats until the destination is reached.
- Guarantees the shortest path without guessing.



Breadth-First Search

- Explores all possible paths step by step.
- Starts at the beginning and checks all nearby points first.
- It moves outward layer by layer, ensuring no path is skipped.
- Don't consider distance or cost.