#### **Introduction to the Programming Assignments**

Control of Mobile Robots: Programming & Simulation Week 1





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#### **Overview**

- The purpose of the programming assignments is to implement concepts from the course on a simulated analogue of a mobile robot.
- All assignments will be completed in a MATLAB-based mobile robot simulator.
- The weekly assignments are optional.
- Each assignment can be submitted for feedback.



# **Bridging the Gap**

- Why are the programming assignments worth your time?
  - 1. They are a unique opportunity to apply the equations in this course to an interesting problem: safely navigating a mobile robot through a cluttered environment.
  - 2. You will learn MATLAB, a powerful tool for engineers.
  - 3. Bonus: If you are building the QuickBot in this course, then everything can be tested on this robot!



# **Programming Assignment for Week 1**

- The objective of this first assignment is to install and familiarize yourself with MATLAB, and run the simulator.
- Go to the "Programming Assignments" section on the course page for detailed instructions.



#### **MATLAB**

- MATLAB is a numerical computing environment and a programming language.
- Thanks to support from MathWorks, a license for MATLAB and all required toolboxes will be available for the duration of the course (Jan. 20 – Mar. 31).
- The "Programming Assignments" section on the course page will provide links to resources for learning MATLAB concepts.

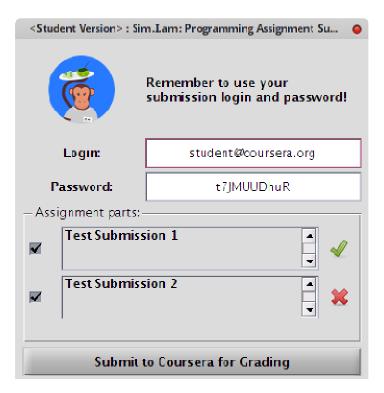


### Sim.I.am

- MATLAB-based simulator for mobile robots.
- Provides a faithful analogue of the robot in this course, QuickBot.
- Includes a detailed user manual for all assignments.



## Grading



- Simple UI for submitting each assignment.
- Points earned in the assignments will <u>not</u> count towards your course grade.



## Help

- If you have any questions, issues, bugs, or concerns, please create a post in the "Discussion Forums" under the "Programming Assignments" section.
- Please include enough information for us or fellow students to help.