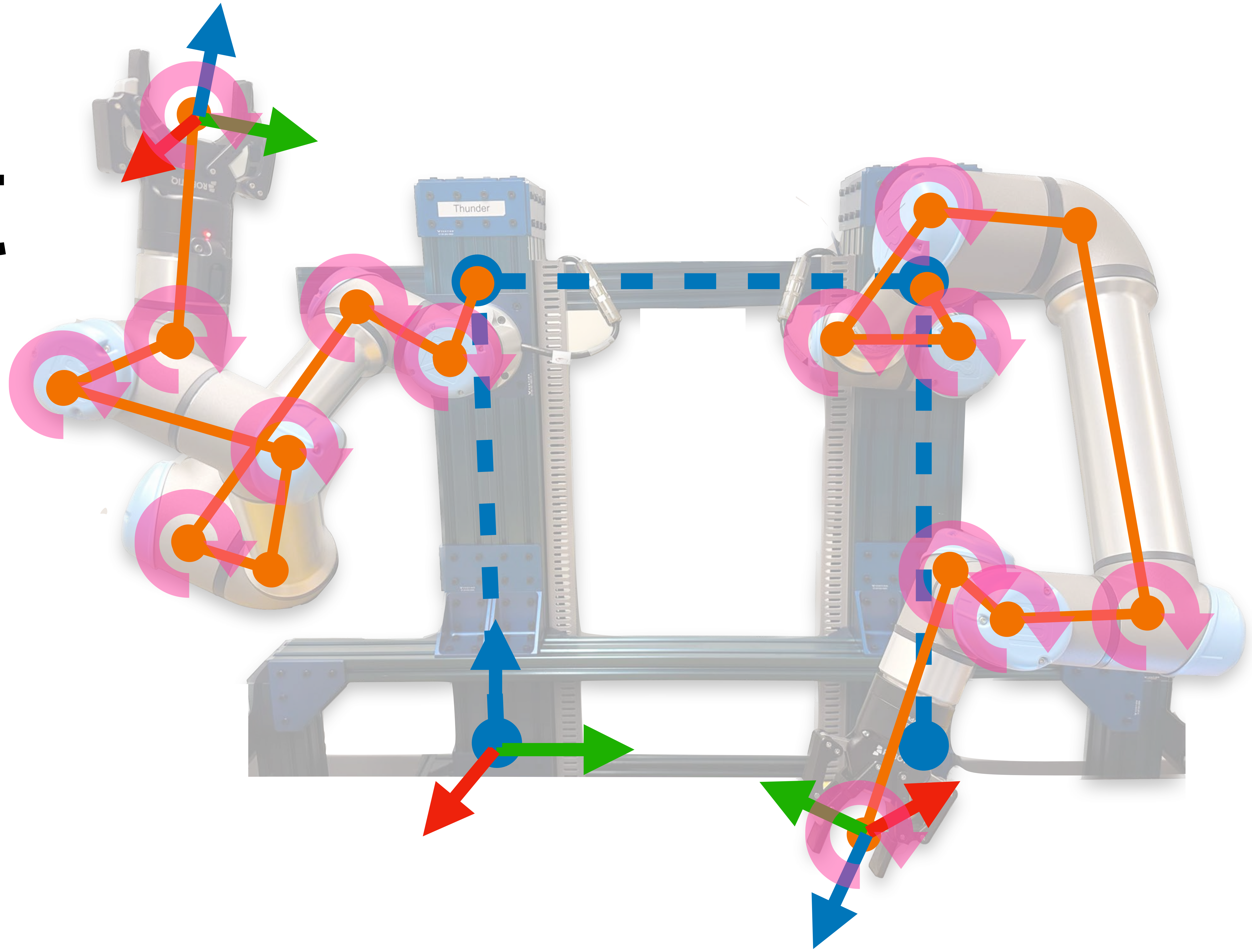
Intro to Intelligent Robotic Systems



CSCI 5551

Spring 2025

University of Minnesota

Welcome to 5551!

Section - 001, 883

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Acknowledgement

- This course builds on and is indebted to materials from:
  - Prof. Chad Jenkins (University of Michigan) and the staff of autorob.org
  - Prof. Dieter Fox (Univ of Washington),
  - Prof. Cyrill Stachniss (Univ of Bonn),
  - Prof. Nikolaos Papanikolopoulos (University of Minnesota),
  - Prof. Junaed Sattar (University of Minnesota)

What are intelligent robotic systems?

What are intelligent robotic systems?

“systems that provide intelligent services and information by interacting with their environment, including human beings, via the use of various sensors, actuators and human interfaces”

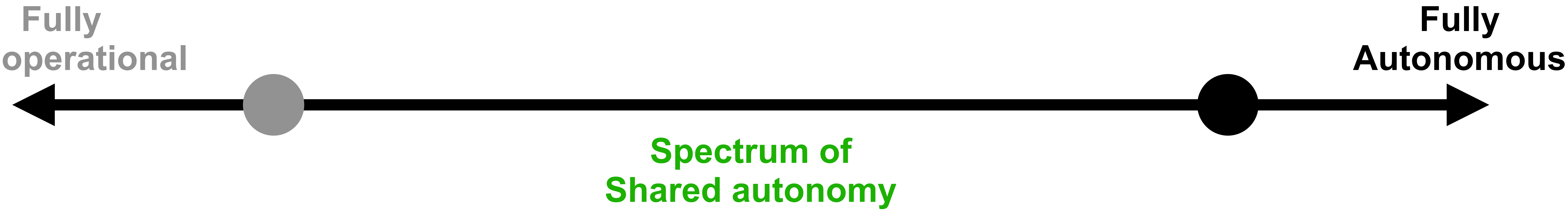
What are intelligent robotic systems?

"systems that provide intelligent services and information by interacting with their environment, including human beings, via the use of various sensors, actuators and human interfaces"

What are intelligent robotic systems?

It is getting very hard to define this term.
For the sake of this course,
let us call this **“ability to operate with some autonomy”**

What are intelligent robotic systems?



What are intelligent robotic systems?

Fully Teleoperational

Fully Autonomous

Spectrum of Shared autonomy

HaptX: https://www.youtube.com/watch?v=uwYtwQtoOh0

What are intelligent robotic systems?

Fully Teleoperational

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Spectrum of Shared autonomy

TUM/IAS group 2012: https://www.youtube.com/watch?v=cTCJSNjTdo0

What are intelligent robotic systems?

…systems that can perform Sense-Plan-Act….

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Zhiqiang Sui et al. 2017

What are intelligent robotic systems?

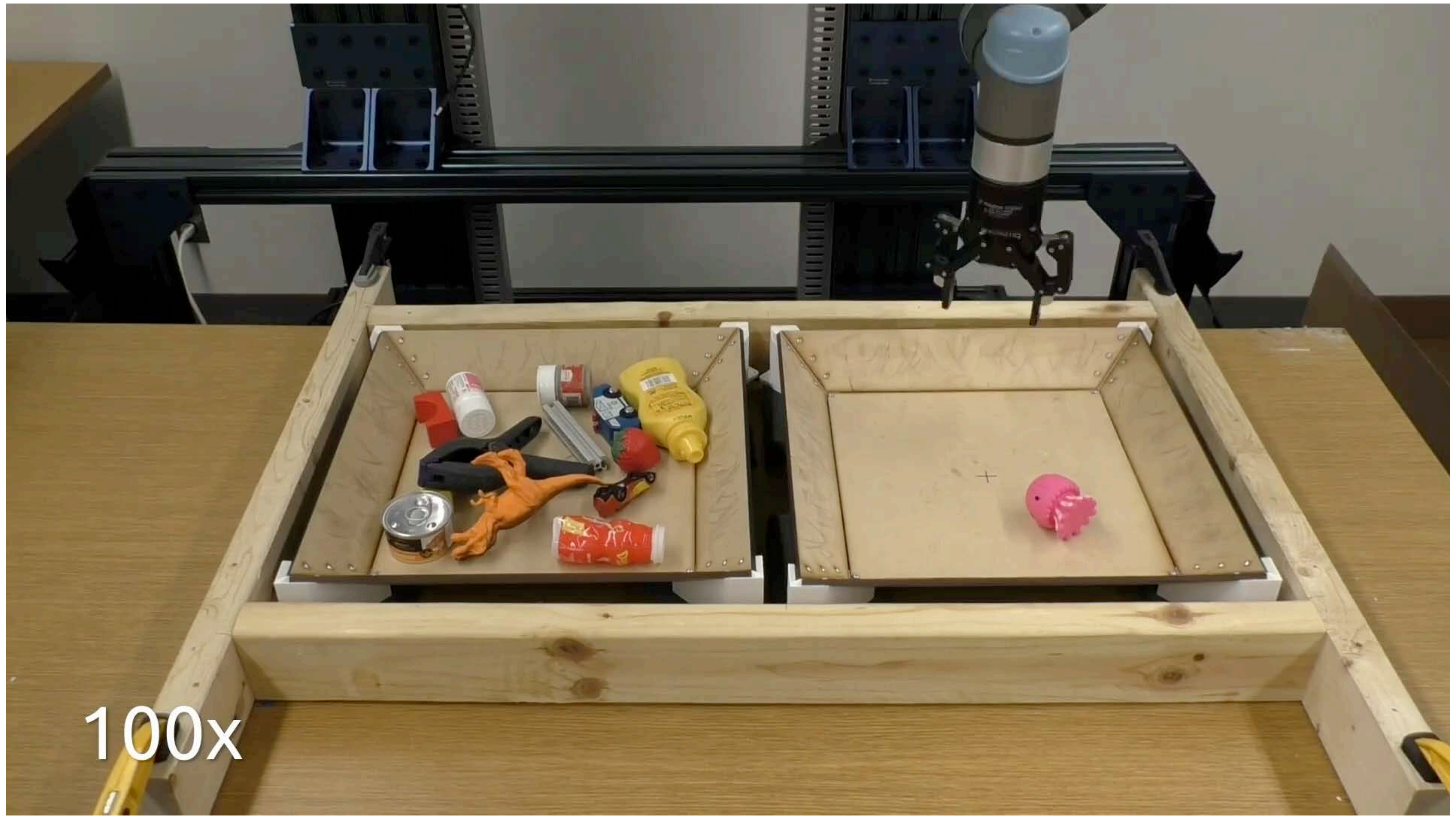
…systems that can perform Sense-Plan-Act….

Zhiqiang Sui et al. 2017

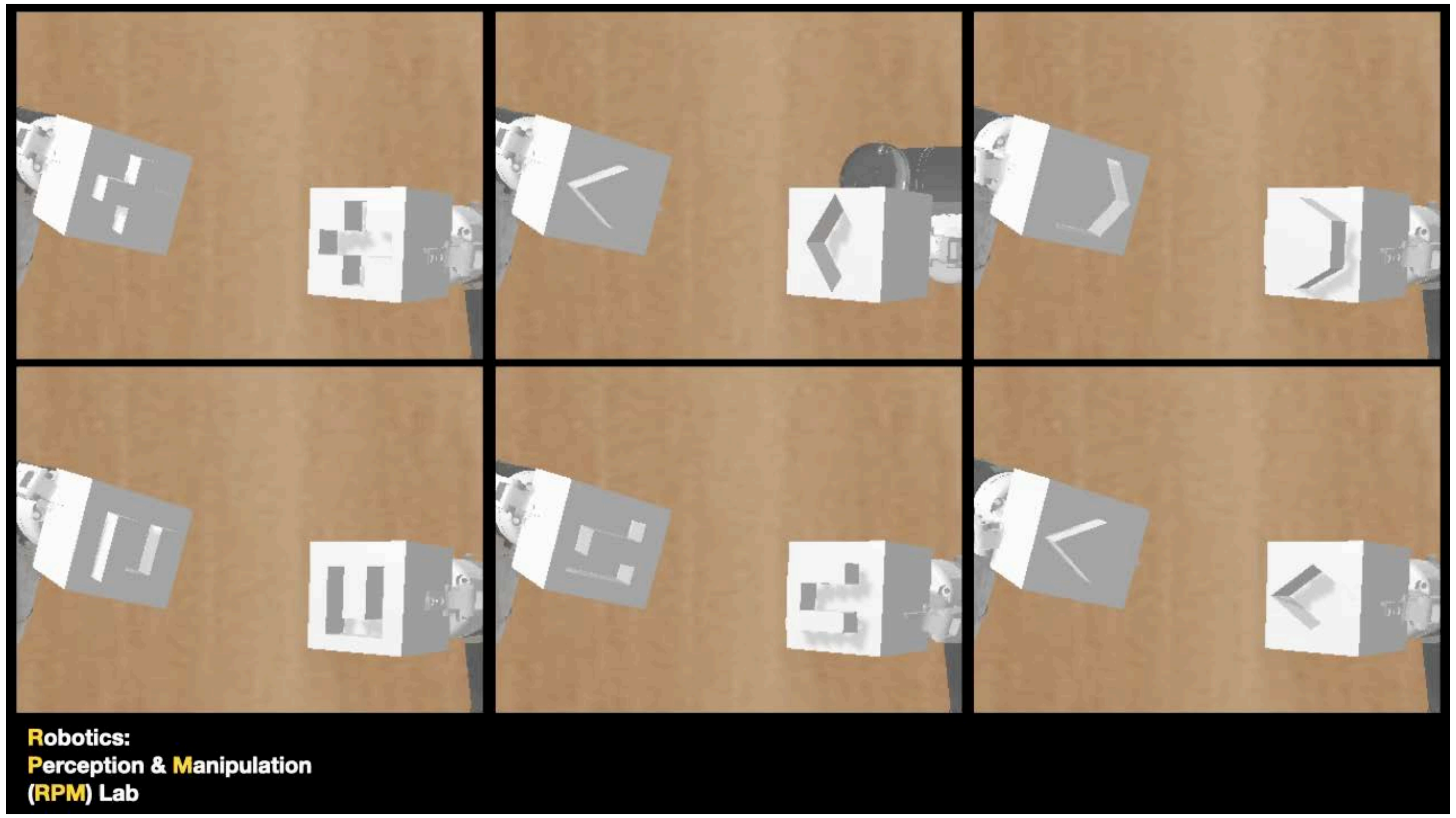
What are intelligent robotic systems?

…systems that can perform Sense-Plan-Act….

… learn skills … transfer these skills … adapt to new environments … work with humans …



Carl Winge et al. 2022



Chahyon Ku et al. 2023

What are intelligent robotic systems?

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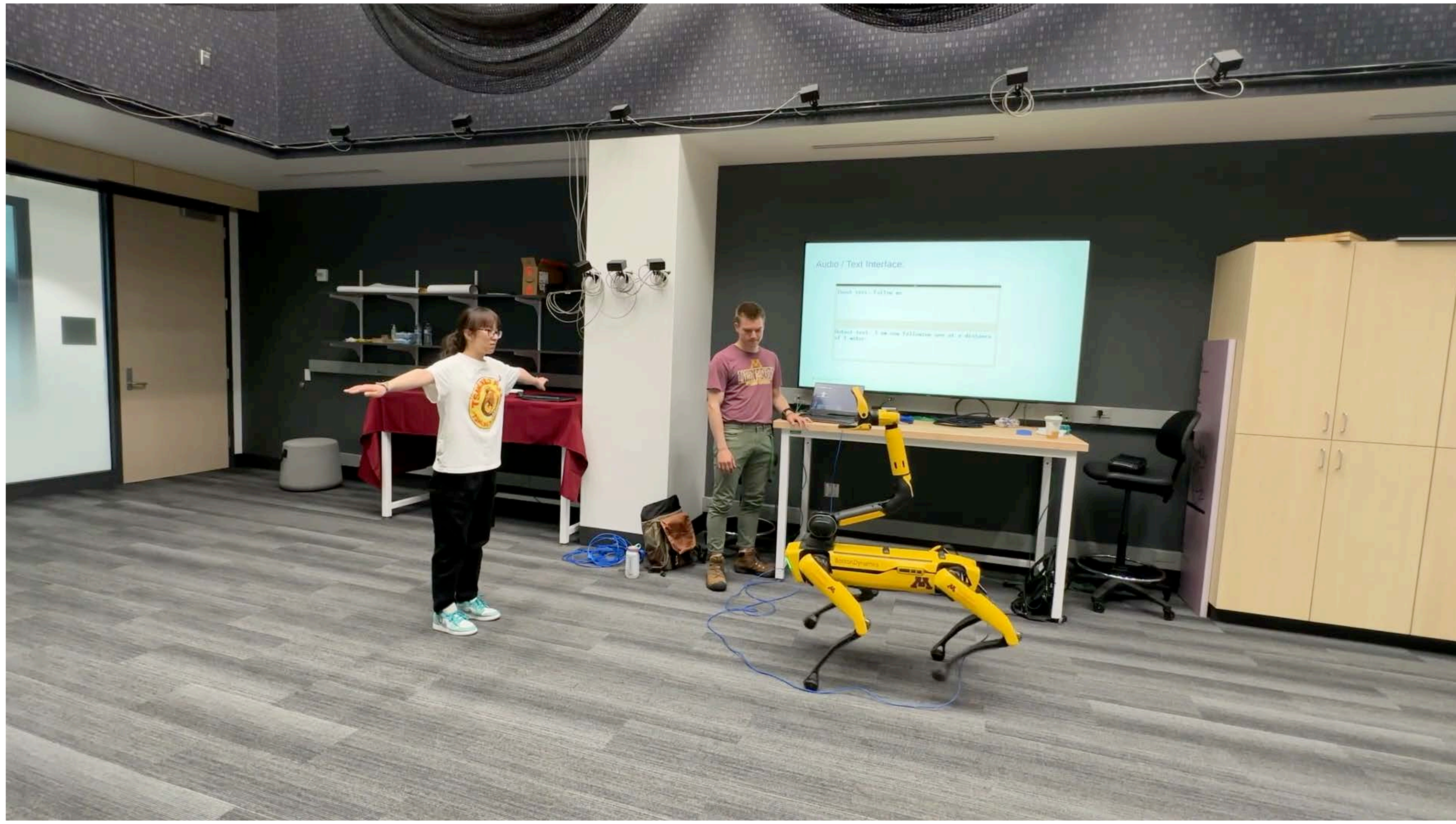
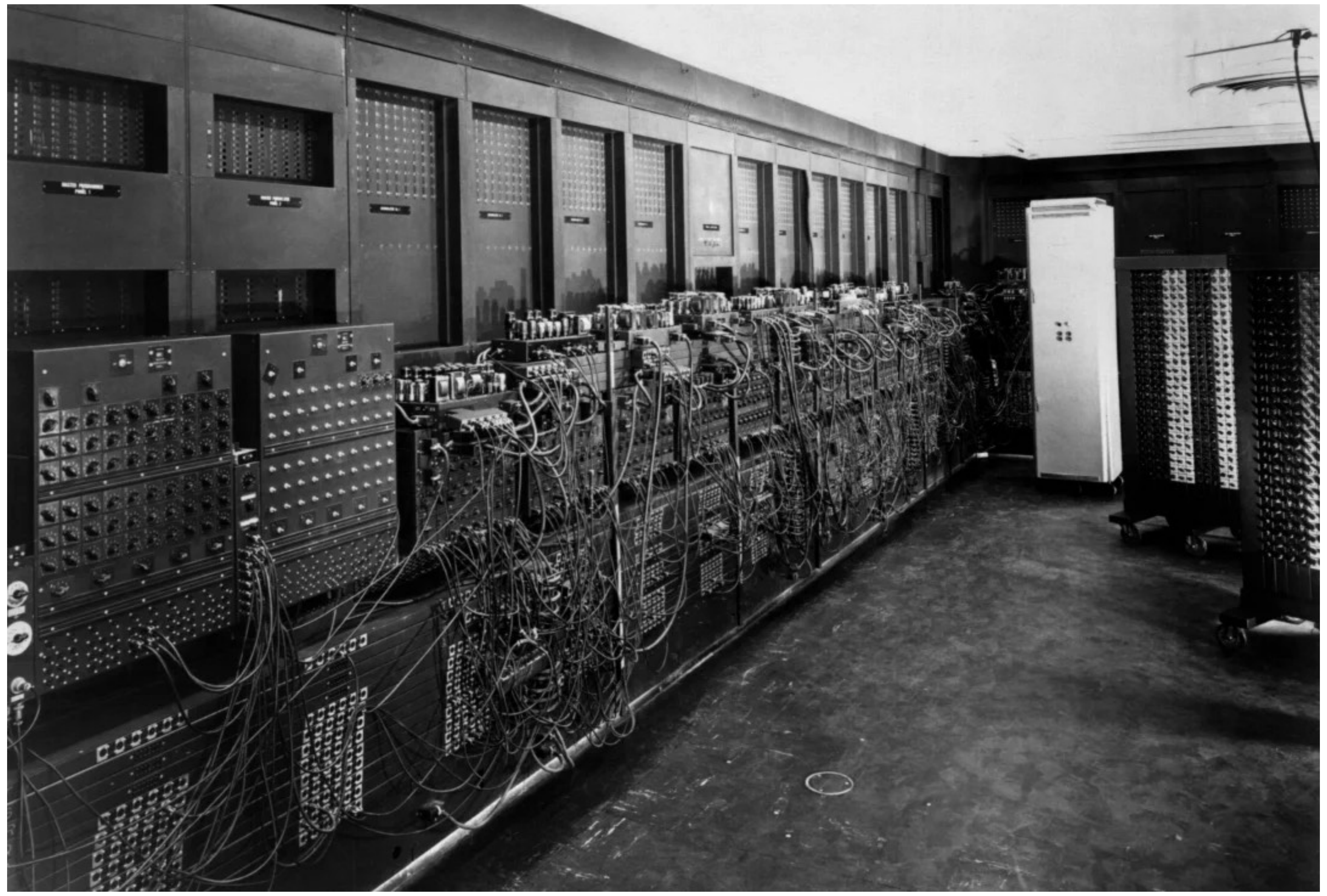
Xun Tu, Bahaa Aldeeb 2023



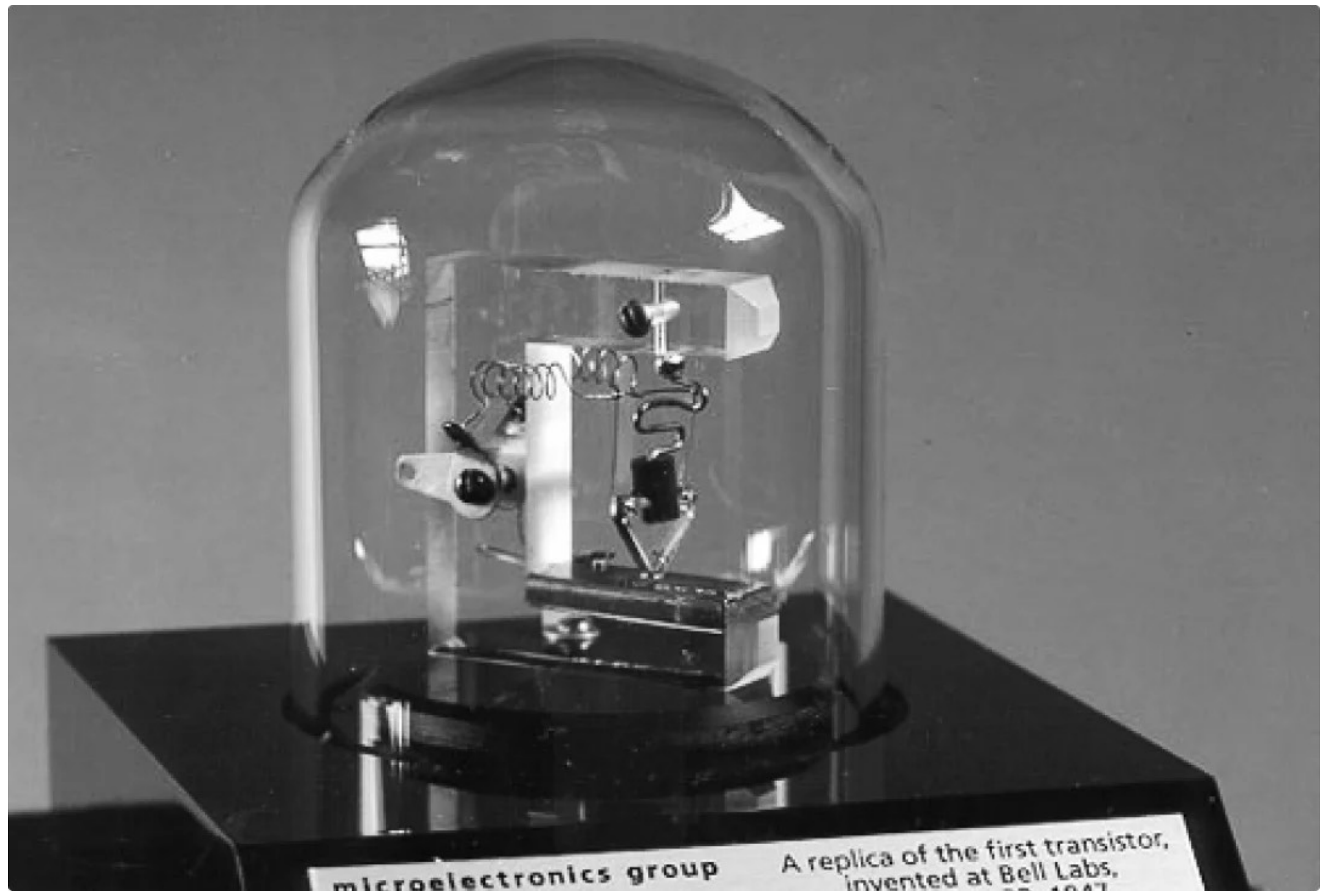
Adam Imdieke, Shirley Su, Xun Tu 2024

History of Computers, AI and Robotics



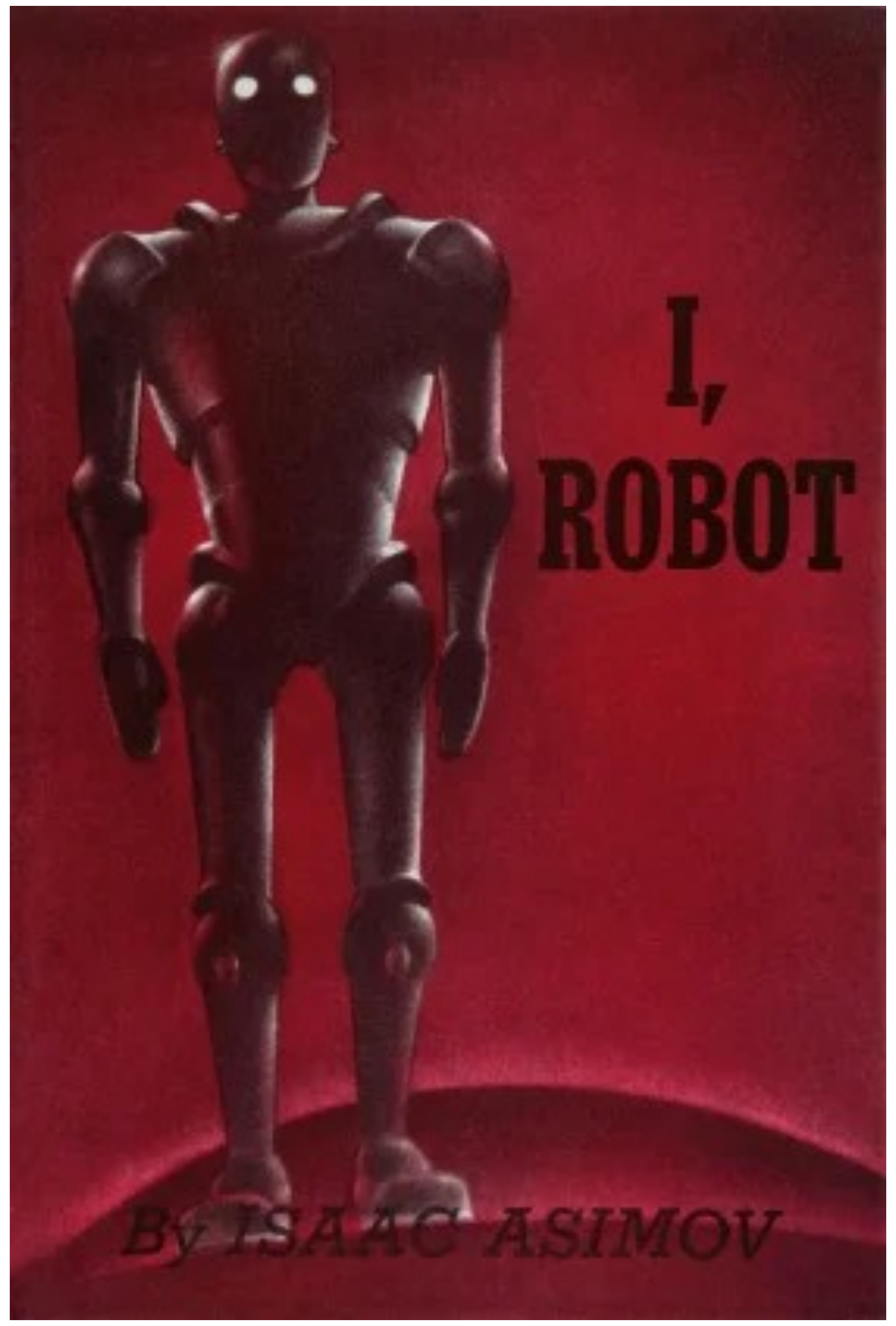
Pennsylvania University professors
John Mauchly and J. Presper Eckert build
the ‘grandfather’ of digital computers, the
Electronic Numerical Integrator and Calculator (ENIAC)

1944



Researchers William Shockley, John Bardeen
and Walter Brattain
at Bell Laboratories invent the transistor.

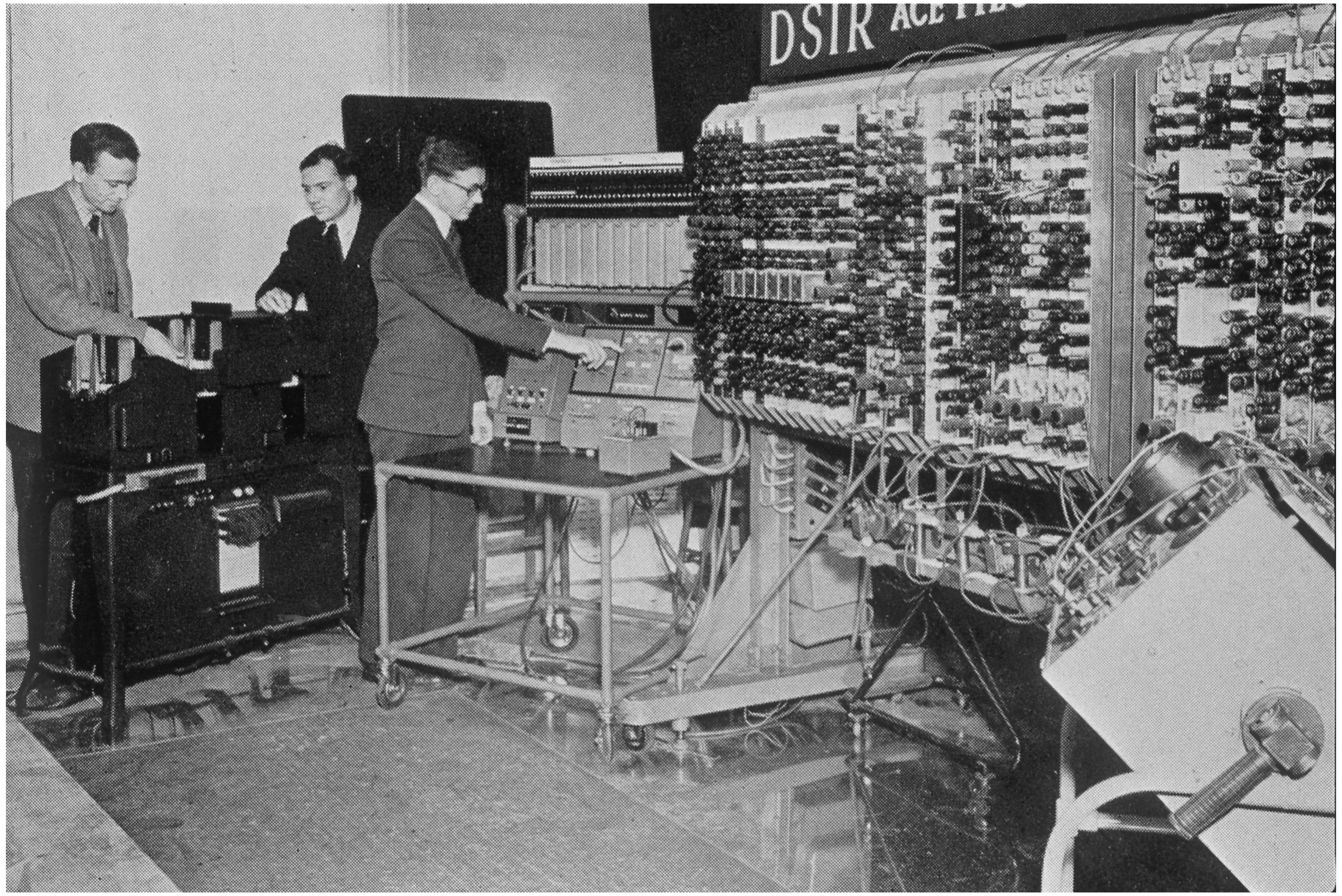
1948



‘I,Robot’ by Issac Asimov is
published, laying the foundations
for the idea of robots in culture.

1950

https://everydayrobots.com/



Alan Turing introduces ‘The Turing Test’ —
a test of a machine's ability to exhibit intelligent behavior
equivalent to, or indistinguishable from, that of a human.

Grace Hopper develops COBOL, the first computer language.
The second, FORTRAN, is developed by a team of
IBM programmers a year later.

1950

1953

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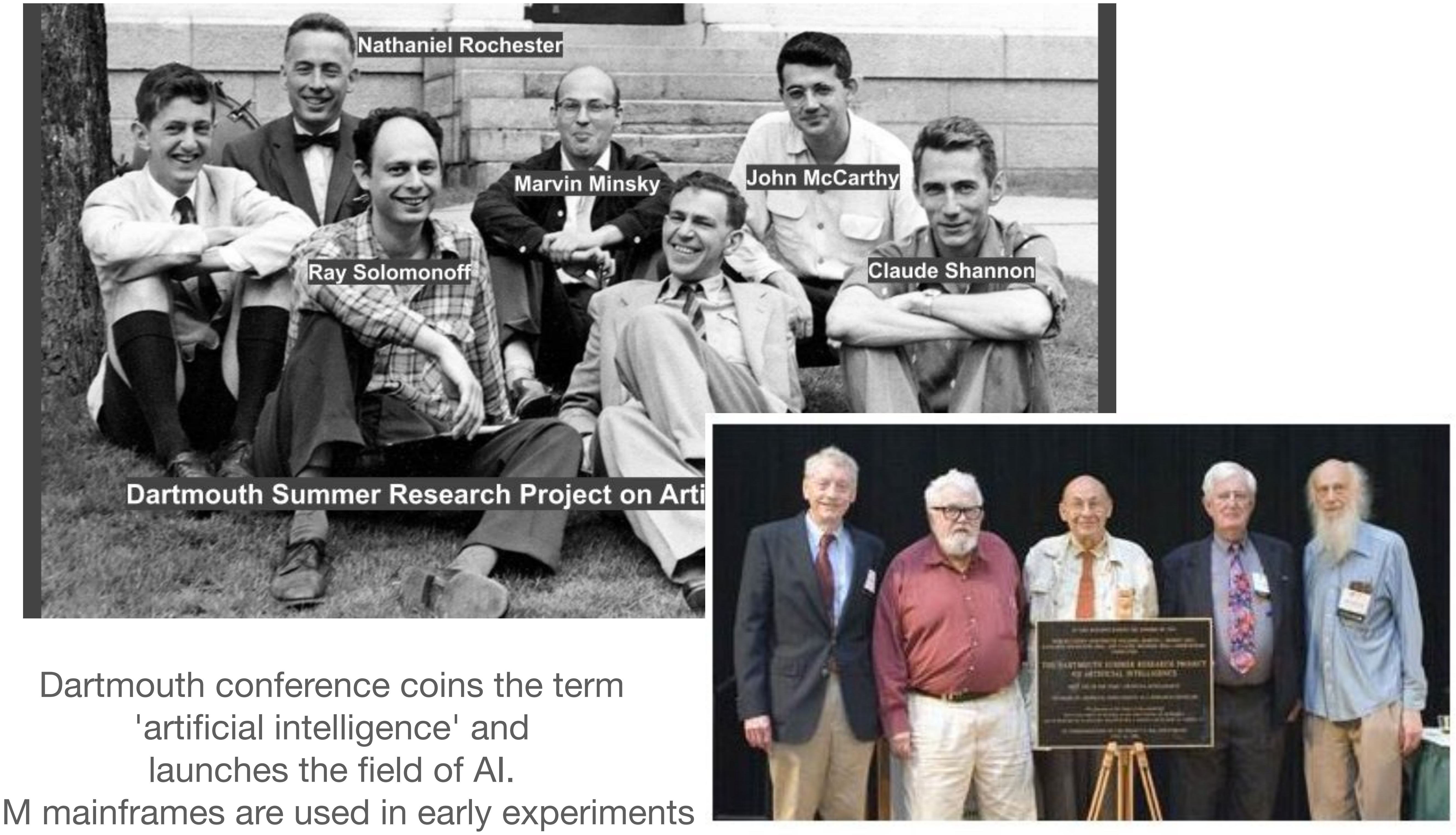
https://everydayrobots.com/



Five of the attendees of the 1956 Dartmouth Summer Research Project on Artificial Intelligence reunited at the July AI@50 conference. From left: Trenchard More, John McCarthy, Marvin Minsky, Oliver Selfridge, and Ray Solomonoff. (Photo by Joseph Mehling '69)

Dartmouth conference coins the term
'artificial intelligence' and
launches the field of AI.
IBM mainframes are used in early experiments

1956

IBM's chairman and CEO, Thomas J. Watson Jr.,
bets the company's future on the IBM Series/360 —
the largest privately-financed commercial project in history.
The risk pays off, changing the computer industry forever.
Work is revolutionized, productivity is enhanced and
countless new tasks become possible.

1964

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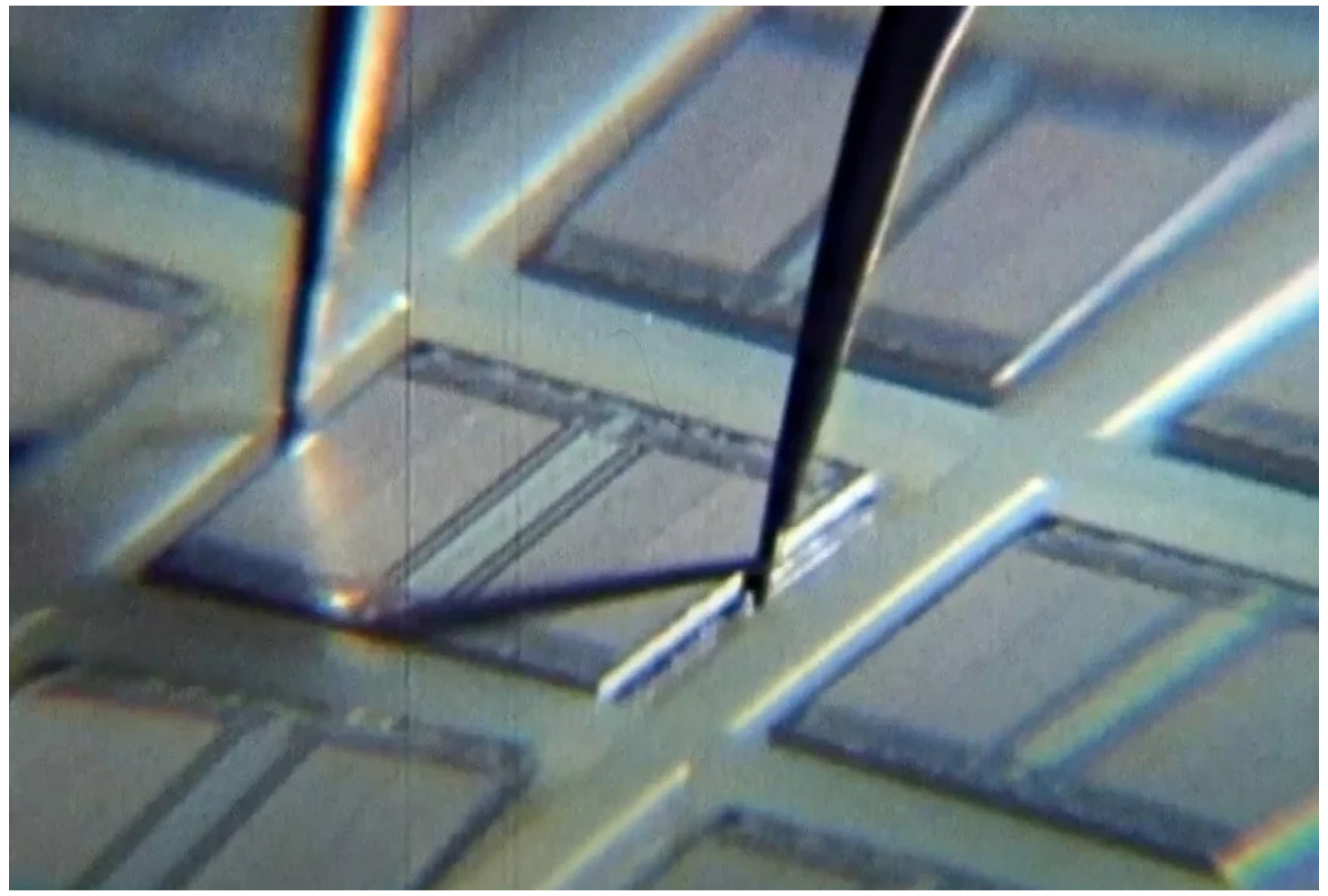

Intel and Ted Hoff introduce the first microprocessor, the Intel 4004.

Intel co-founder, Gordon Moore, theorizes that computing would dramatically increase in power, and decrease in relative cost, at an exponential pace. The insight, known as Moore's Law, becomes the golden rule for the electronics industry, and a springboard for innovation.

Steve Wozniak and Steve Jobs release the Apple 1

A year later, Apple releases the Apple II

1971

1976

1977

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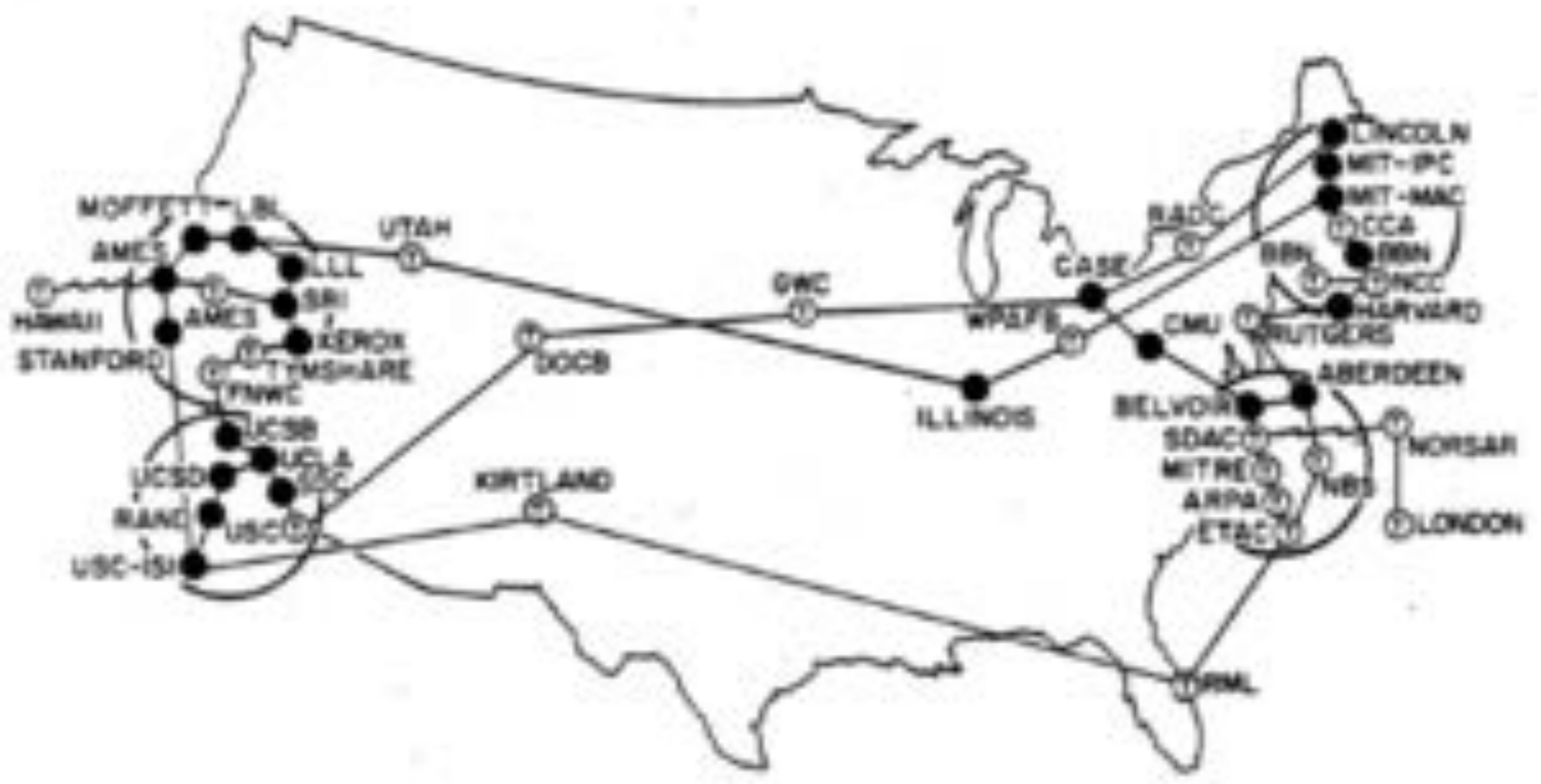
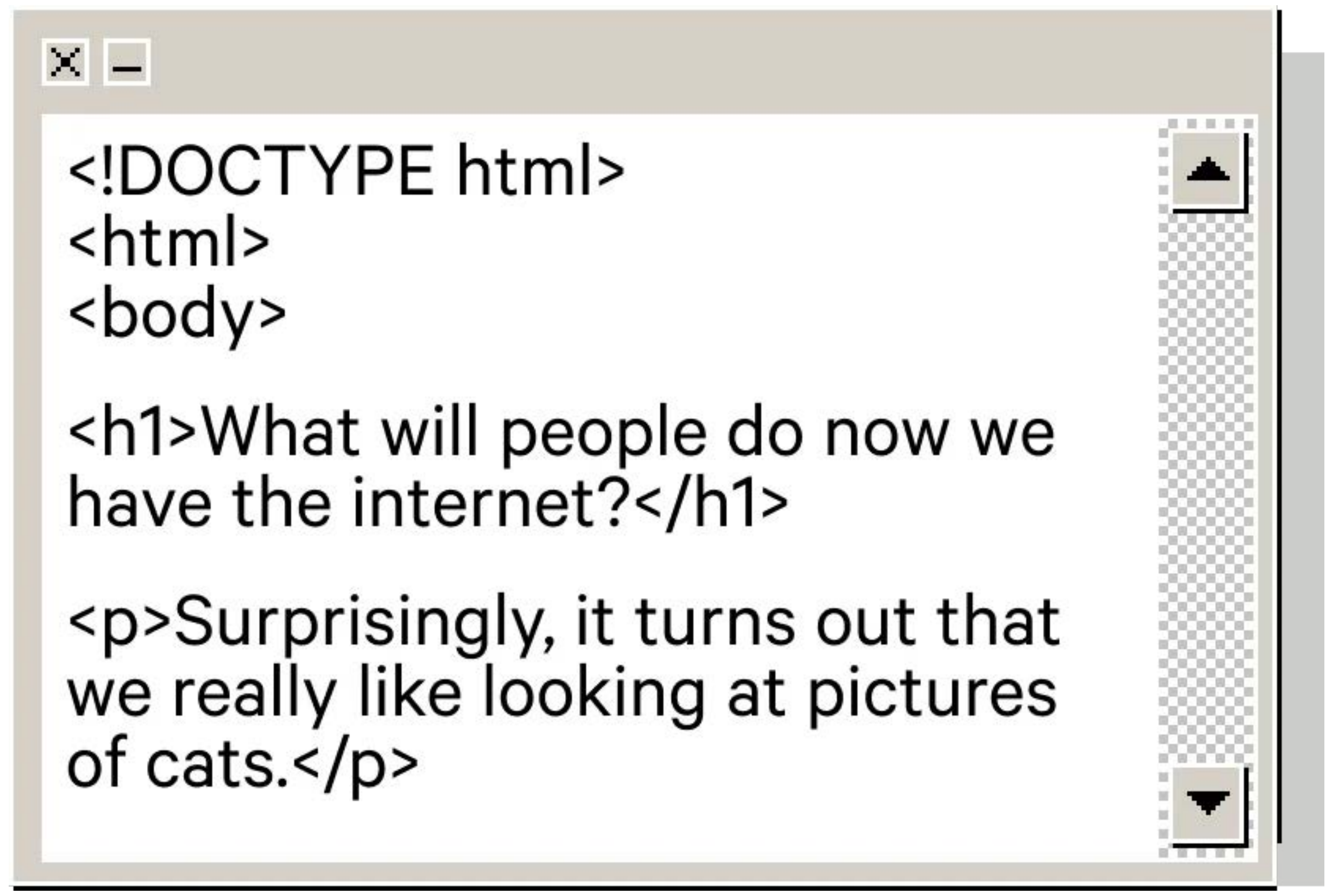


The U.S. Defense Department funds the first experimental computer network— ARPANET. It connects computers everywhere, and is a forerunner to the internet.



```
<!DOCTYPE html>
<html>
<body>

<h1>What will people do now we
have the internet?</h1>

<p>Surprisingly, it turns out that
we really like looking at pictures
of cats.</p>
```

Tim Berners-Lee and his colleagues at CERN develop hypertext markup language (HTML) and the uniform resource locator (URL), giving birth to the first incarnation of the World Wide Web.

IBM's Deep Blue Computer, a form of AI, beats reigning world chess champion Gary Kasparov.

1966

1995

1997

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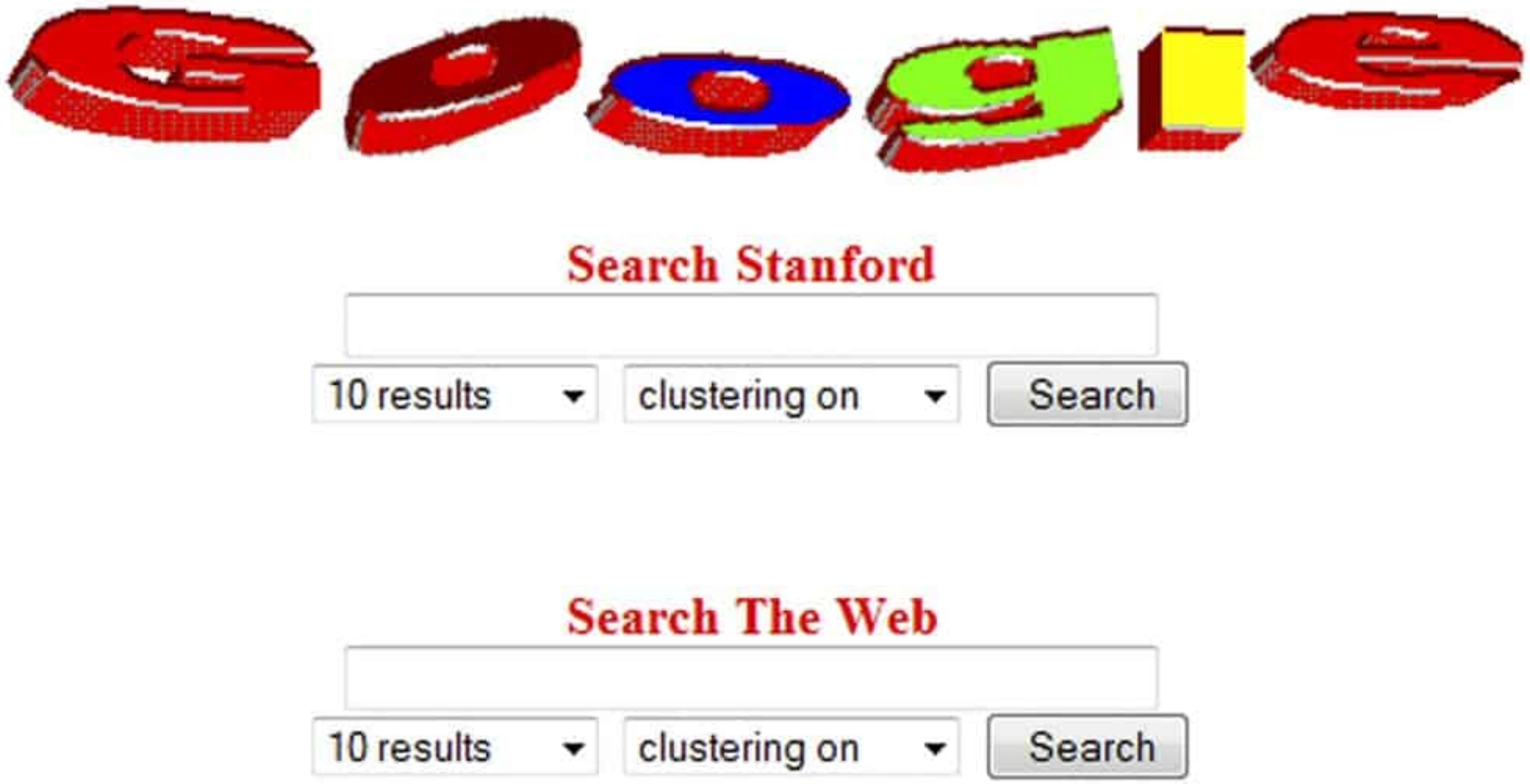

Larry Page & Sergey Brin, two computer science graduate students from Stanford University, pioneer a new way to search for and find information on the web. They call their invention ‘Google’.

Four founders start a company called ‘Android

1998

2003

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Steve Jobs unveils the iPhone at Macworld

Gmail by Google

Google Maps

Google Docs

Search becomes intuitive.
Maps are intelligent.
Work is more productive than ever

2007

https://i.insider.com/587374fadd0895e1148b47e7?width=1136&format=jpeg
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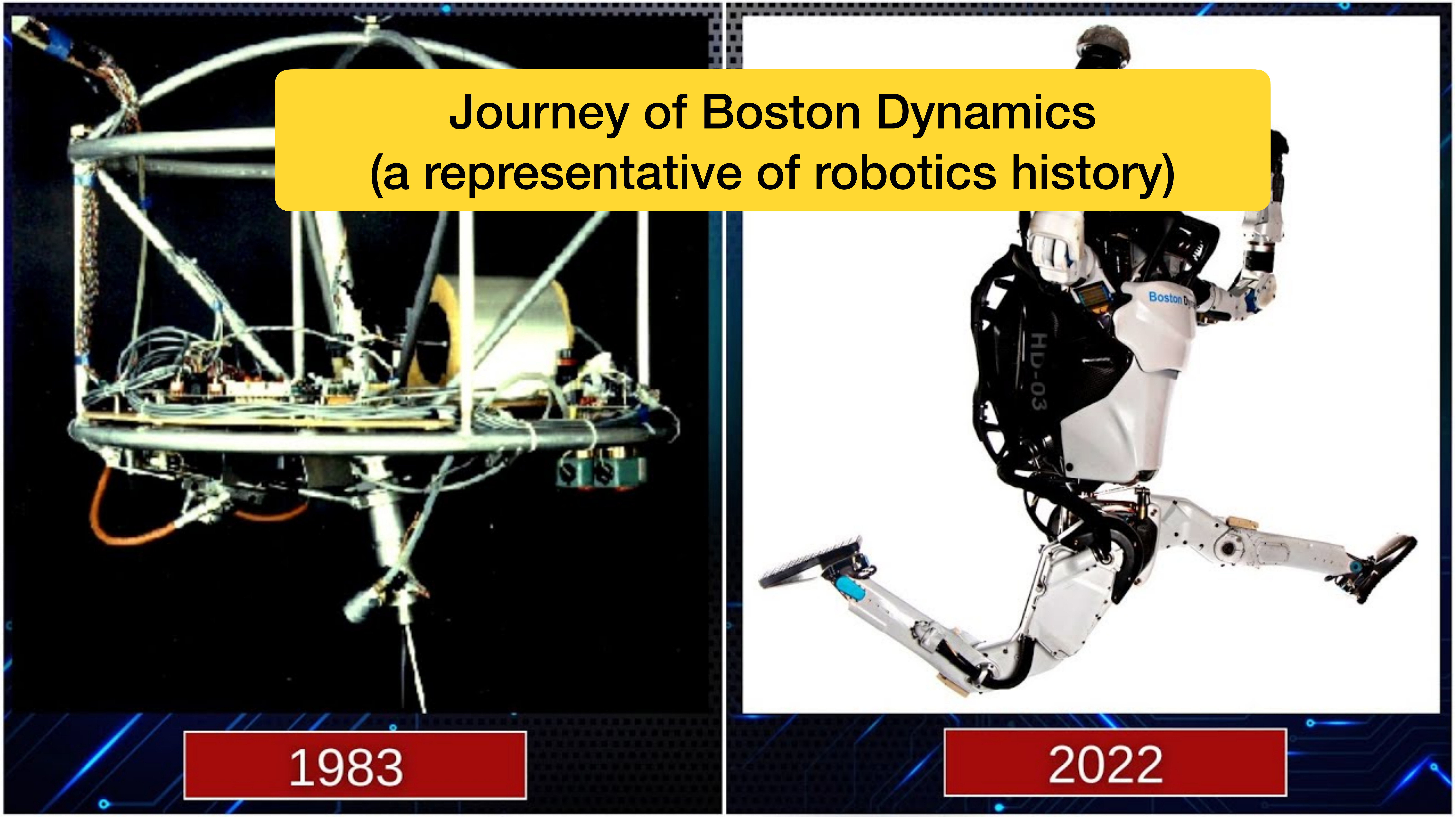
So, this is computing and AI…
What was happening in robotics?

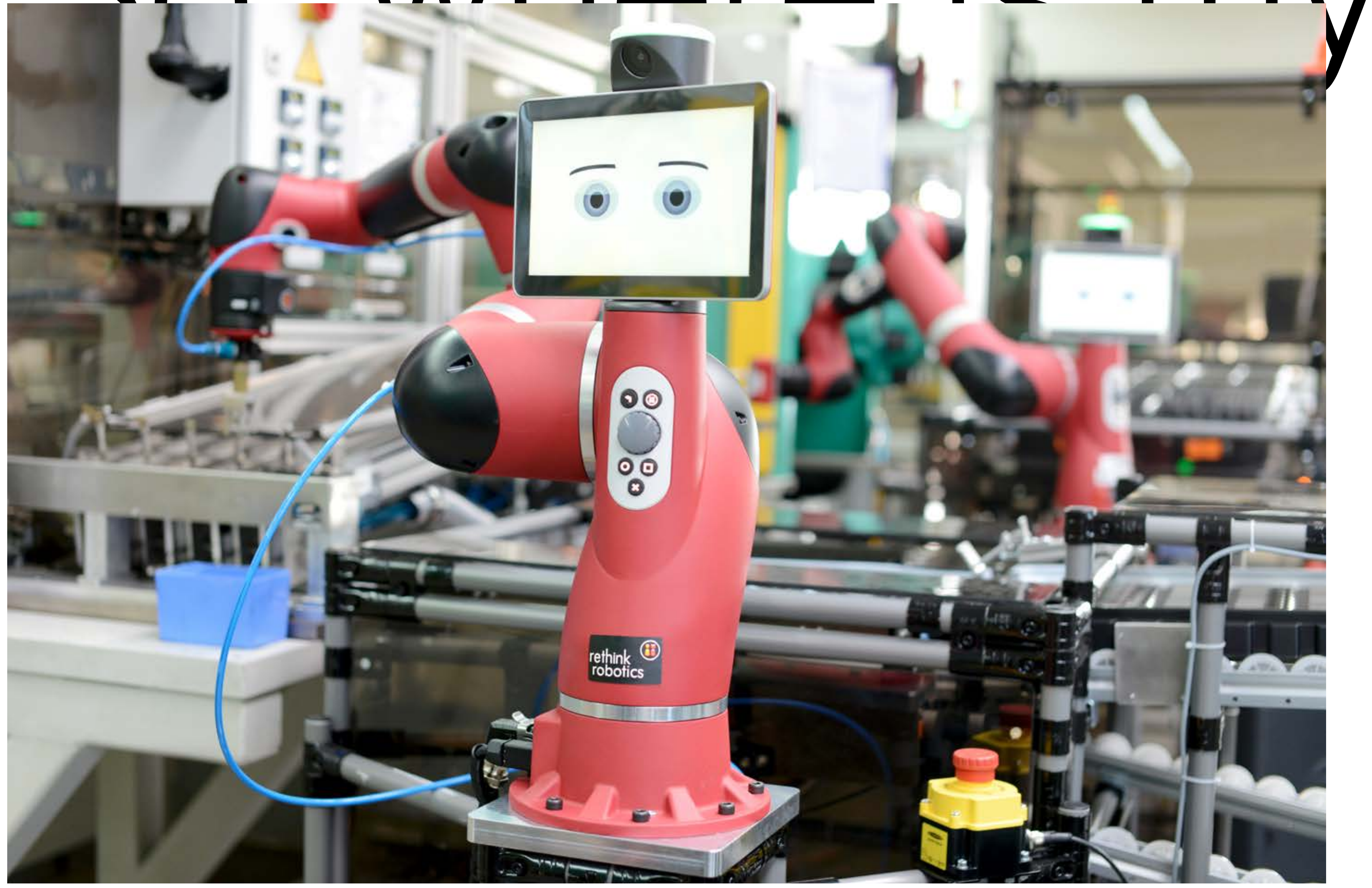
Journey of Boston Dynamics
(a representative of robotics history)



https://www.youtube.com/watch?v=_EZQx87DyzM

So, where is my robot?

So, where is my robot?



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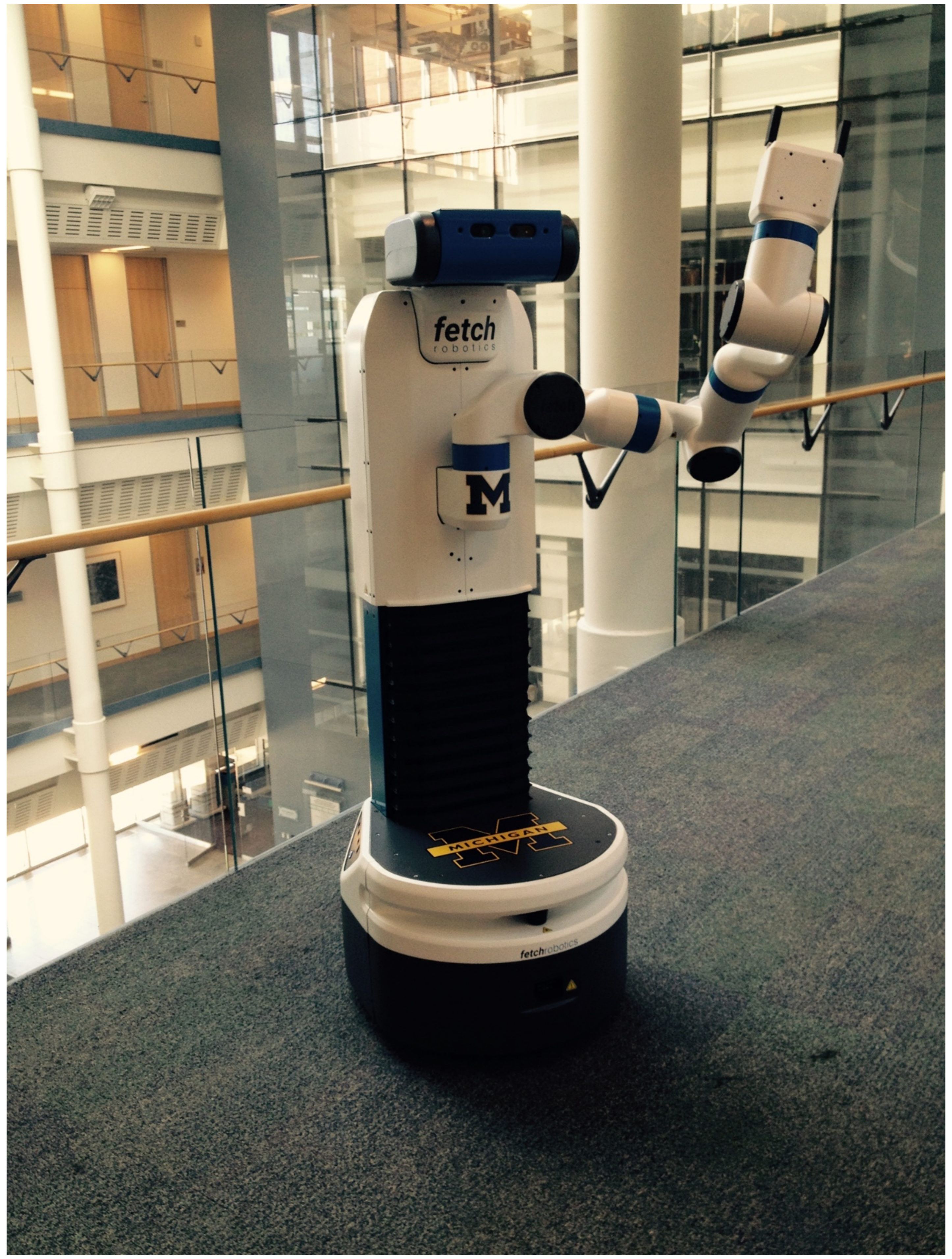
Mobile Manipulation Robots



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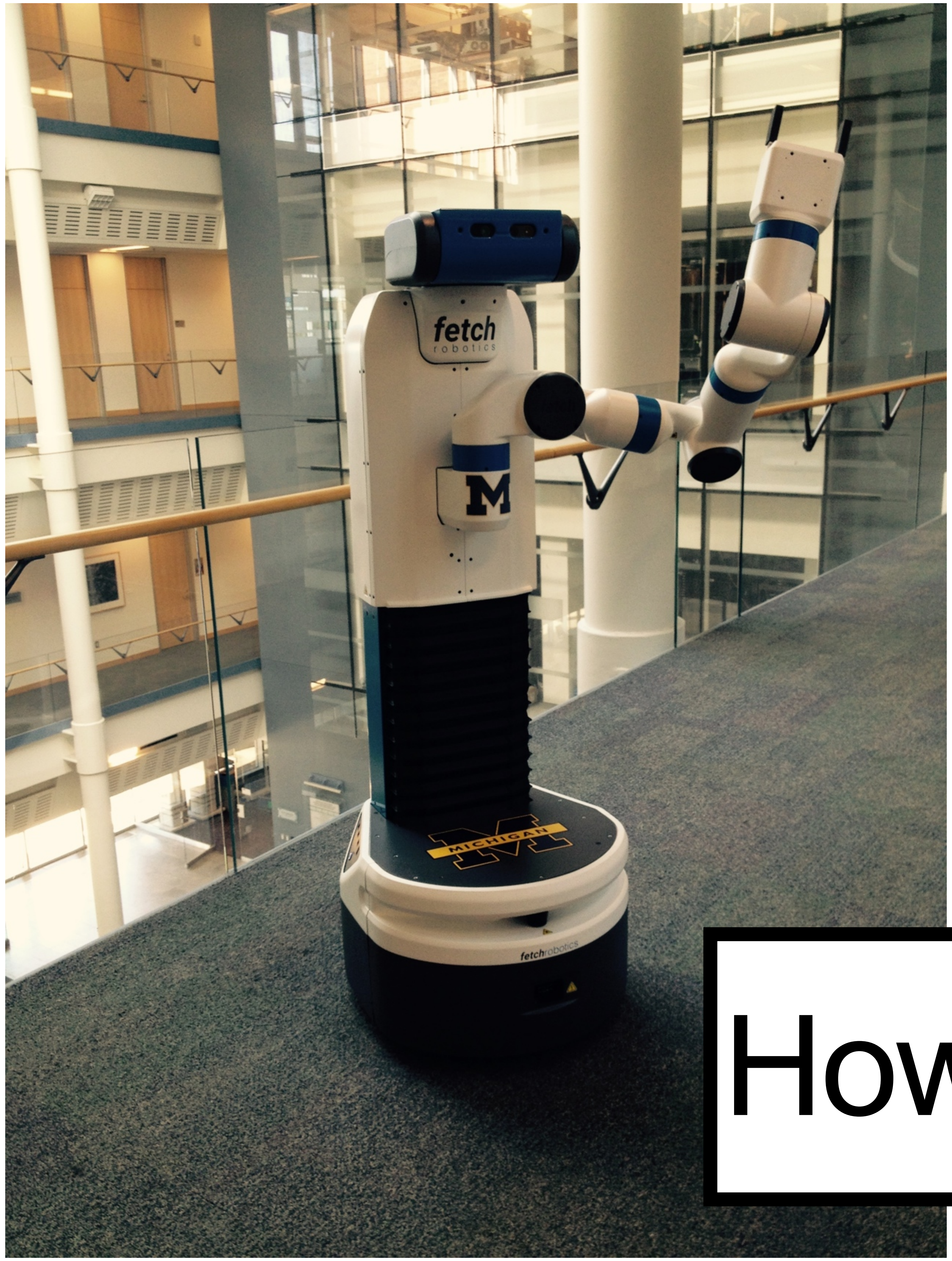

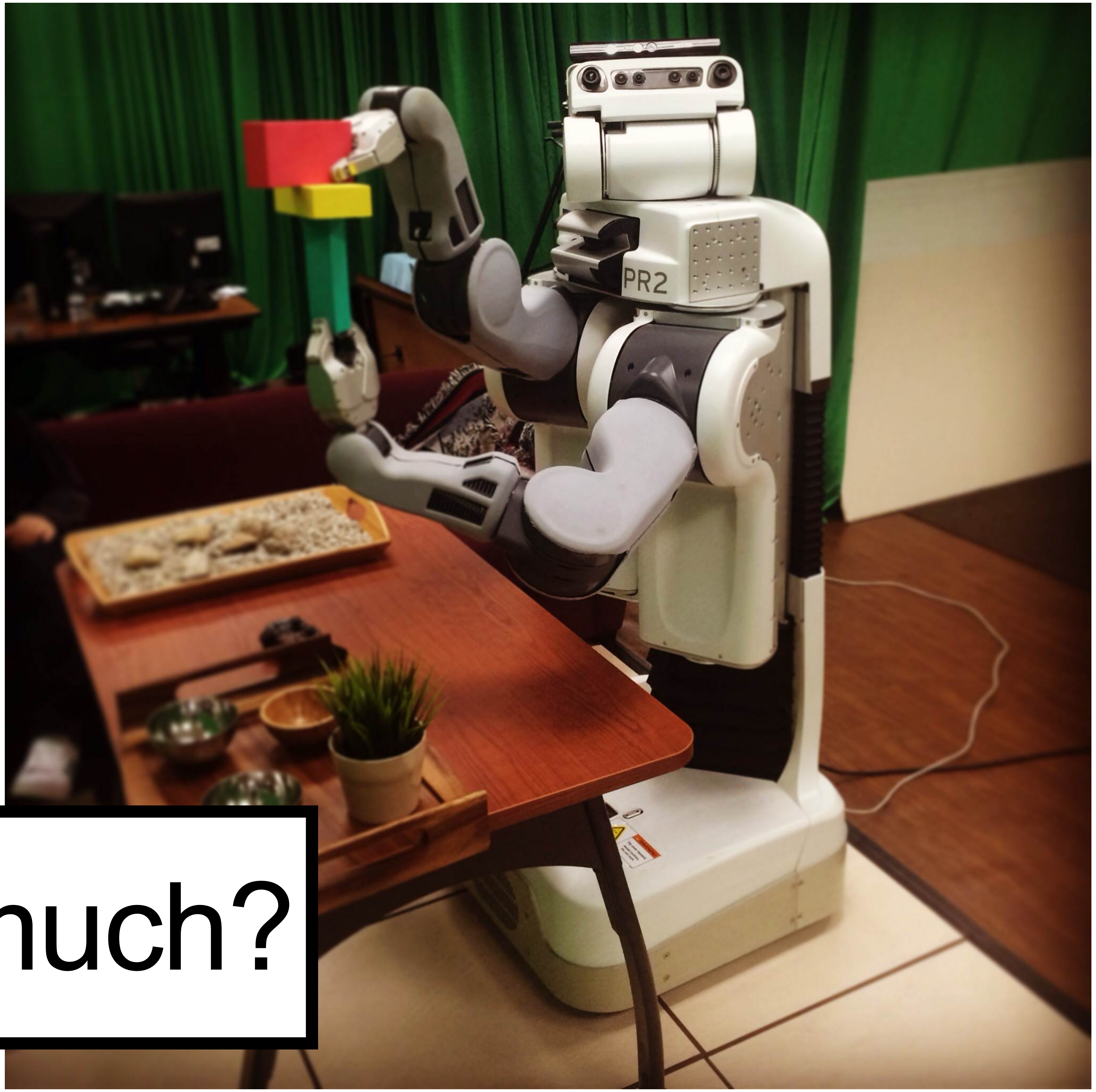

How much?

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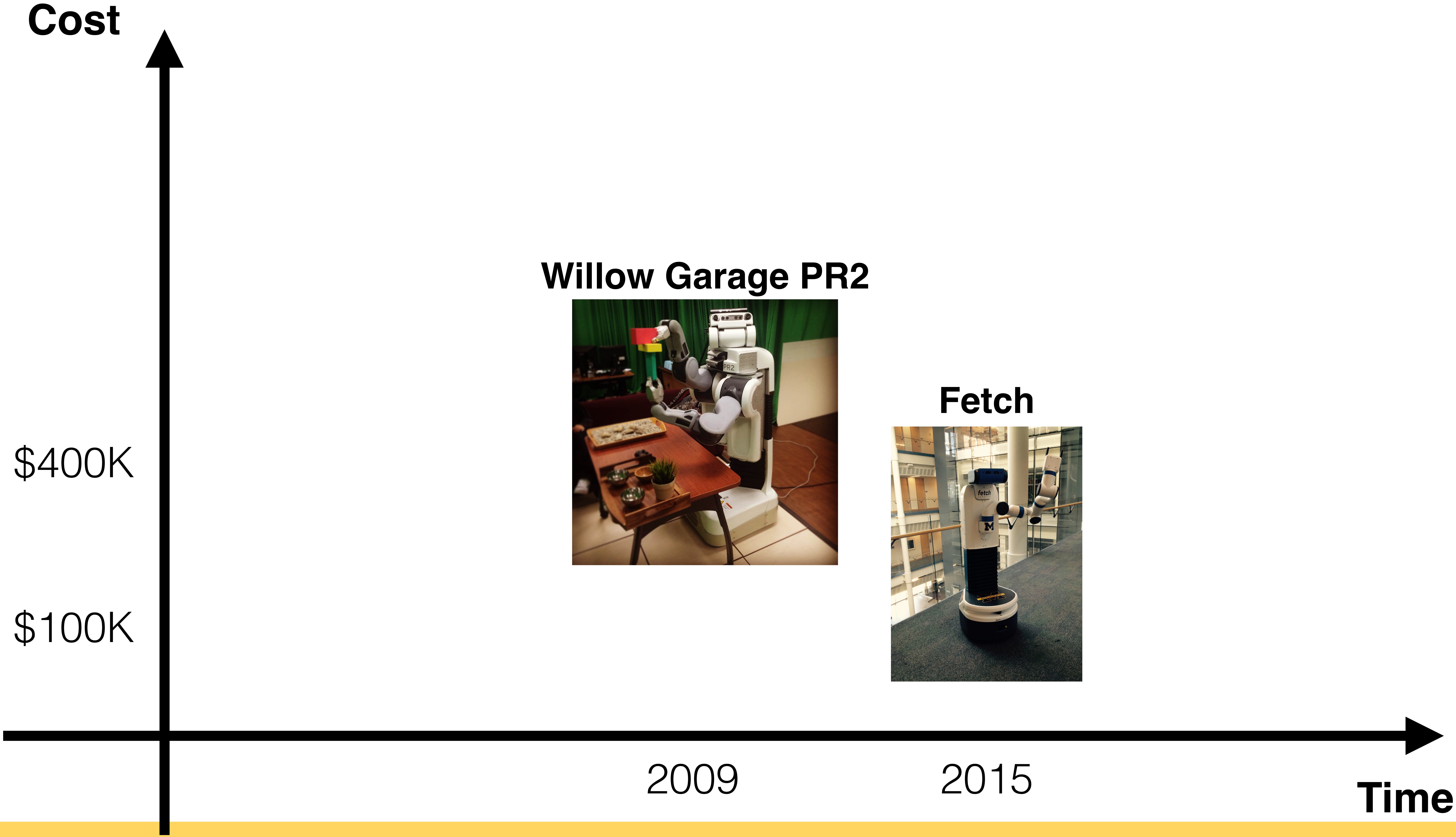

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2002

$400K

$100K

Willow Garage PR2

Fetch

2009

2015

Time

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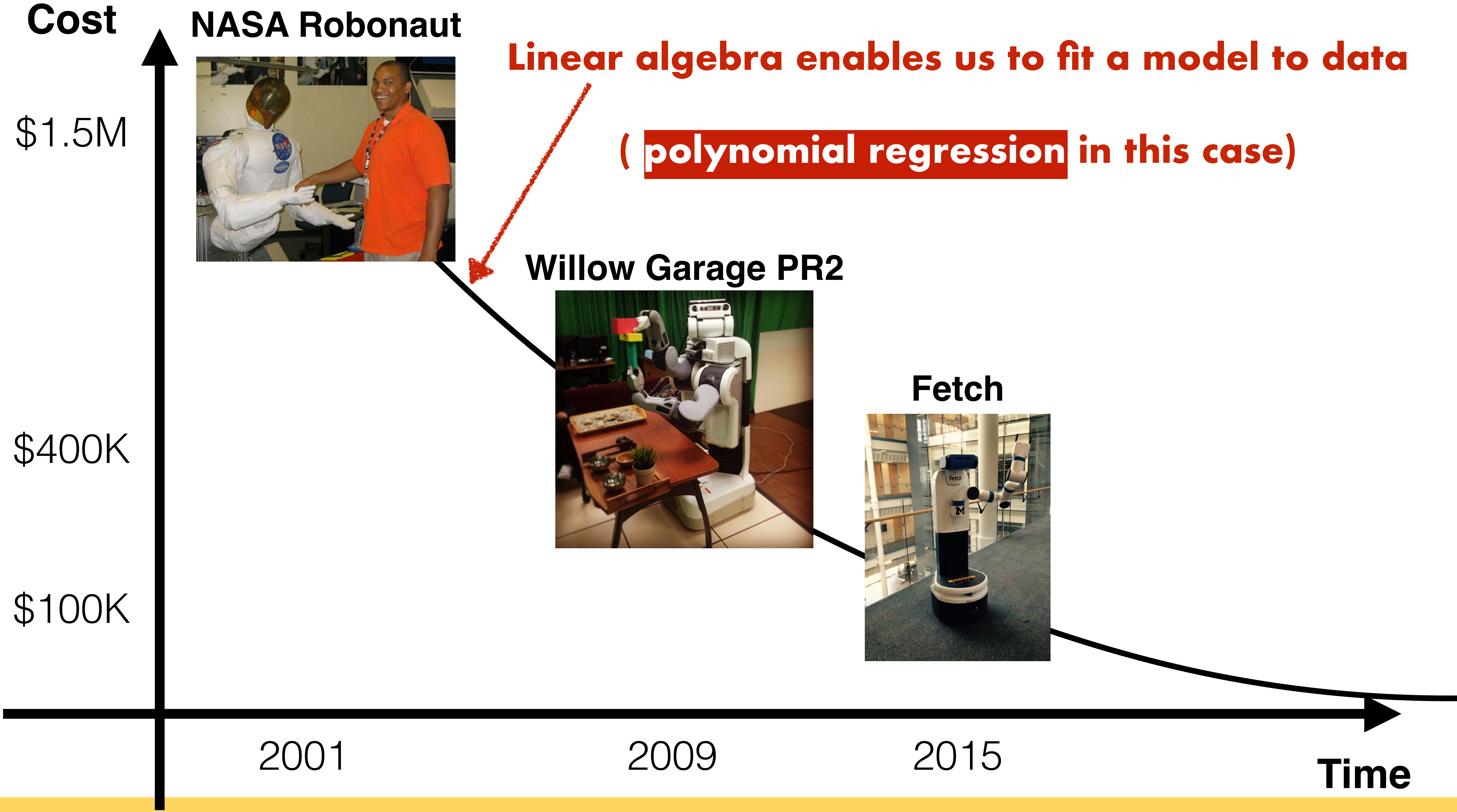
Linear algebra enables us to fit a model to data

(polynomial regression in this case)



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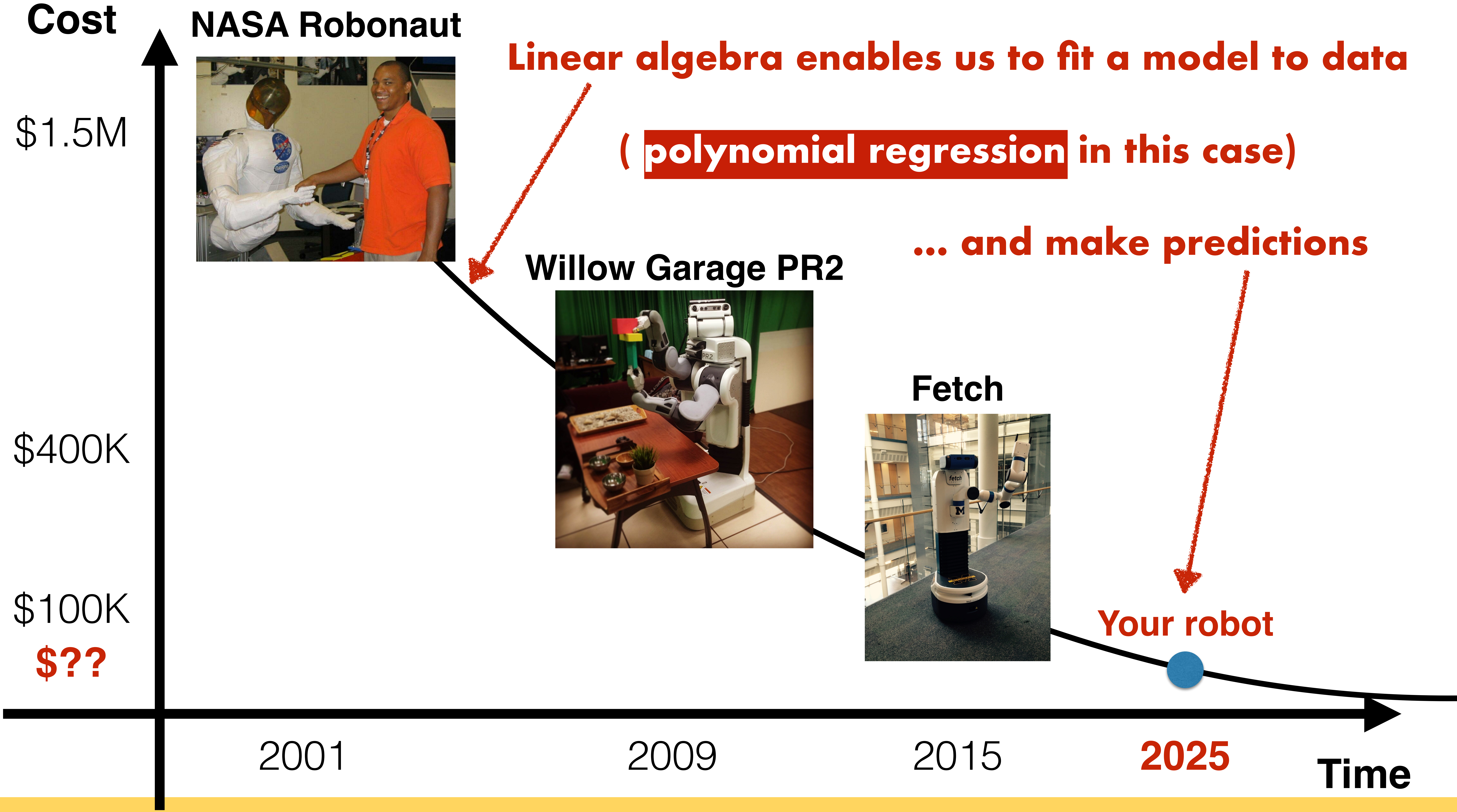

Linear algebra enables us to fit a model to data

(**polynomial regression** in this case)

... and make predictions

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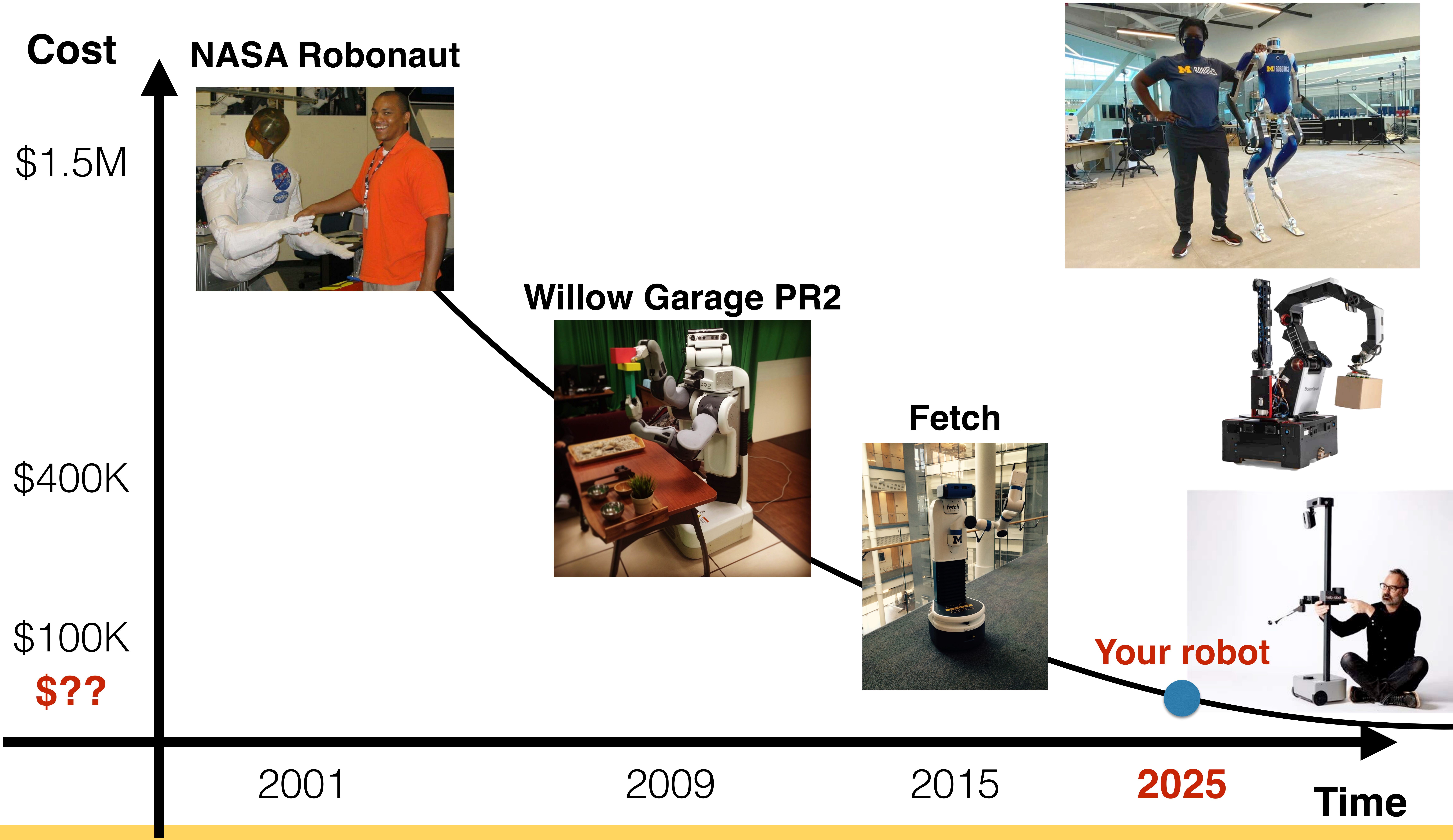

Cost

$1.5M

$400K

$100K

$??

NASA Robonaut

Willow Garage PR2

Fetch

Your robot

2001

2009

2015

2025

Time

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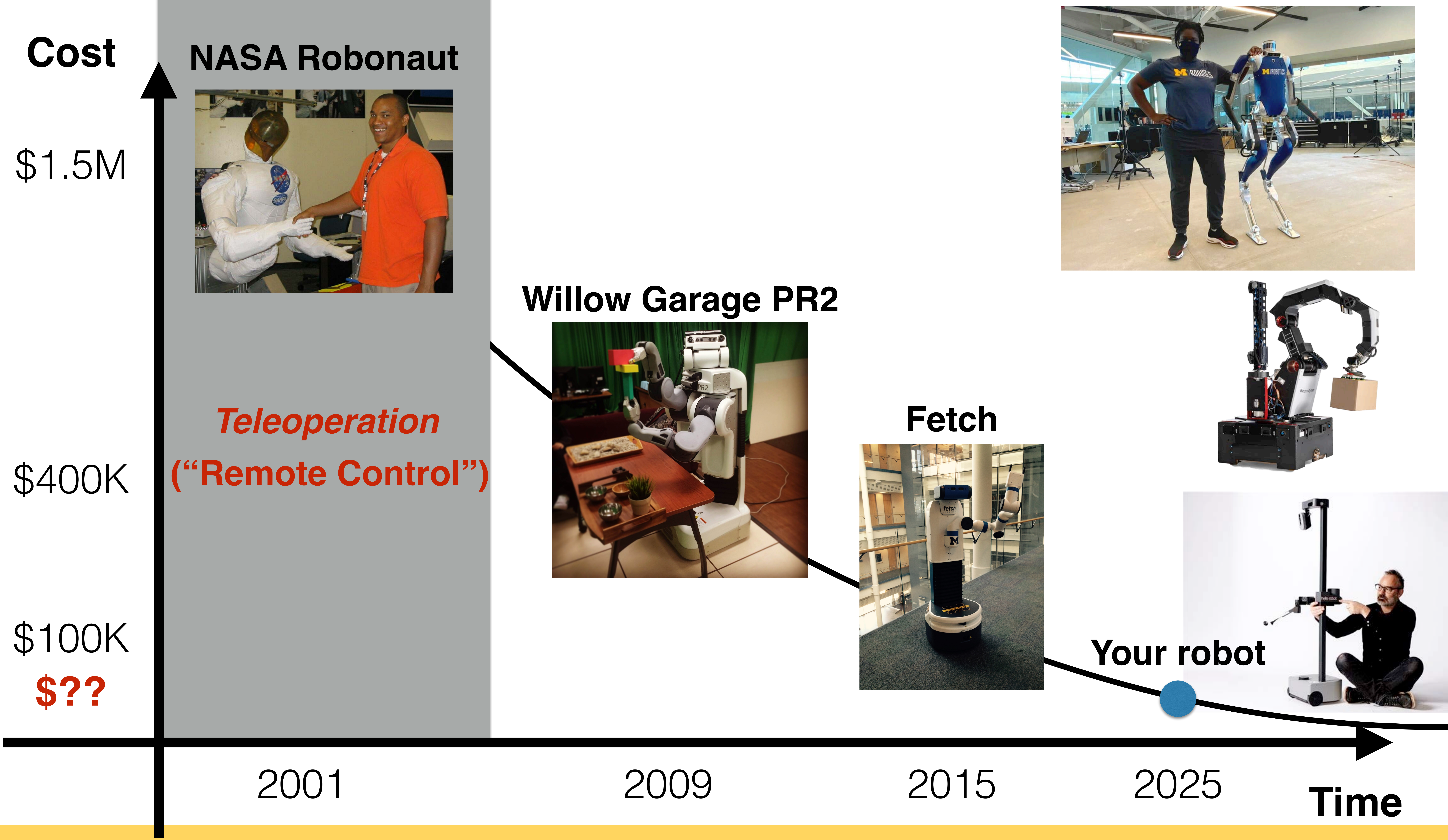

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$100K

$??

NASA Robonaut

Teleoperation

(“Remote Control”)

Willow Garage PR2

Fetch

Your robot

2001

2009

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2025

Time

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Cost

$1.5M

$400K

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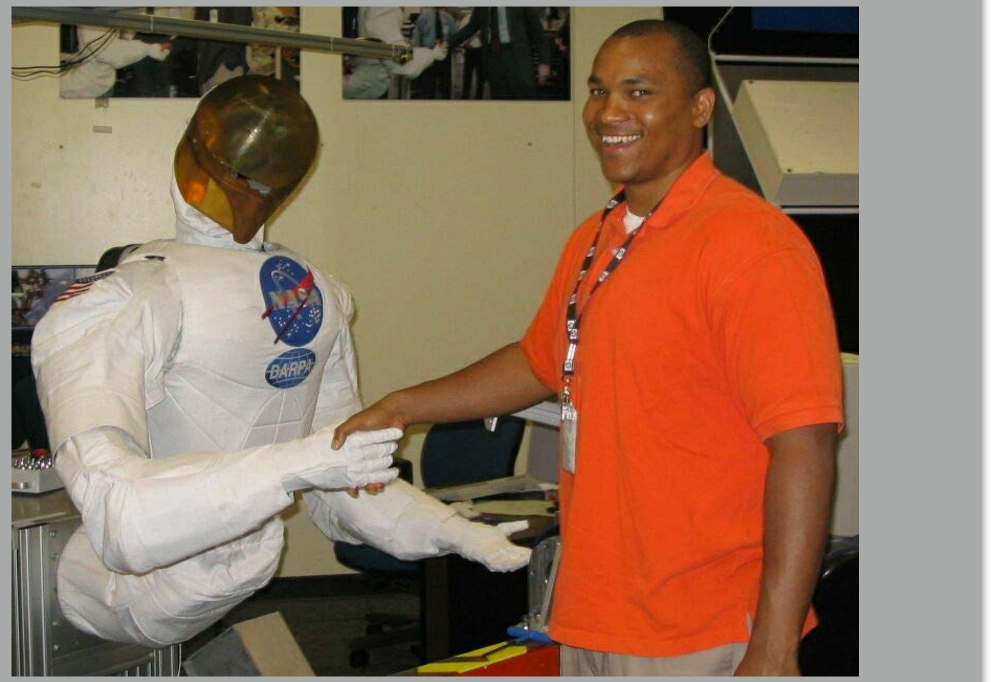
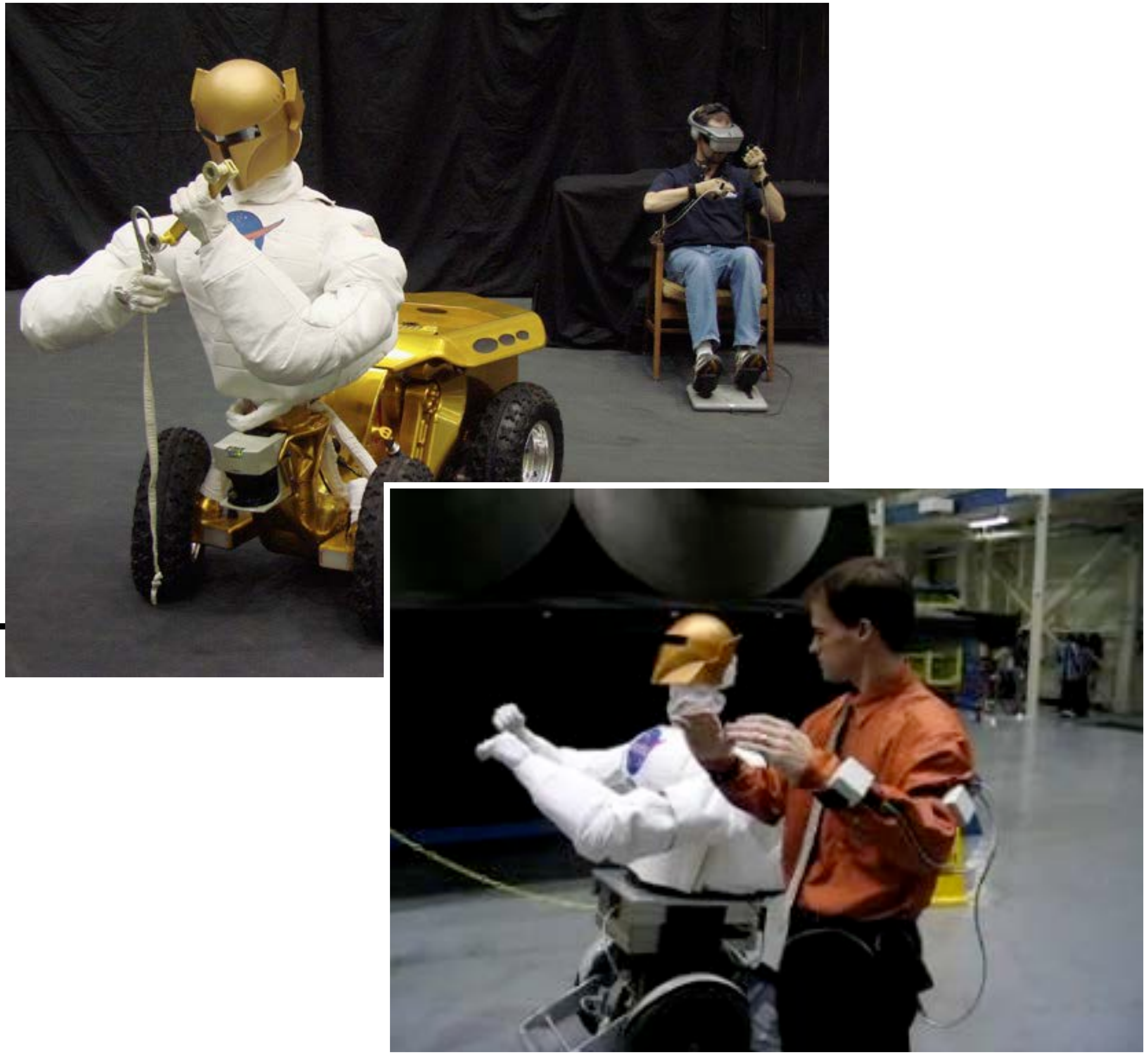
$??

NASA Robonaut



Teleoperation

("Remote Control")



2001

2009

2015

2025

Time

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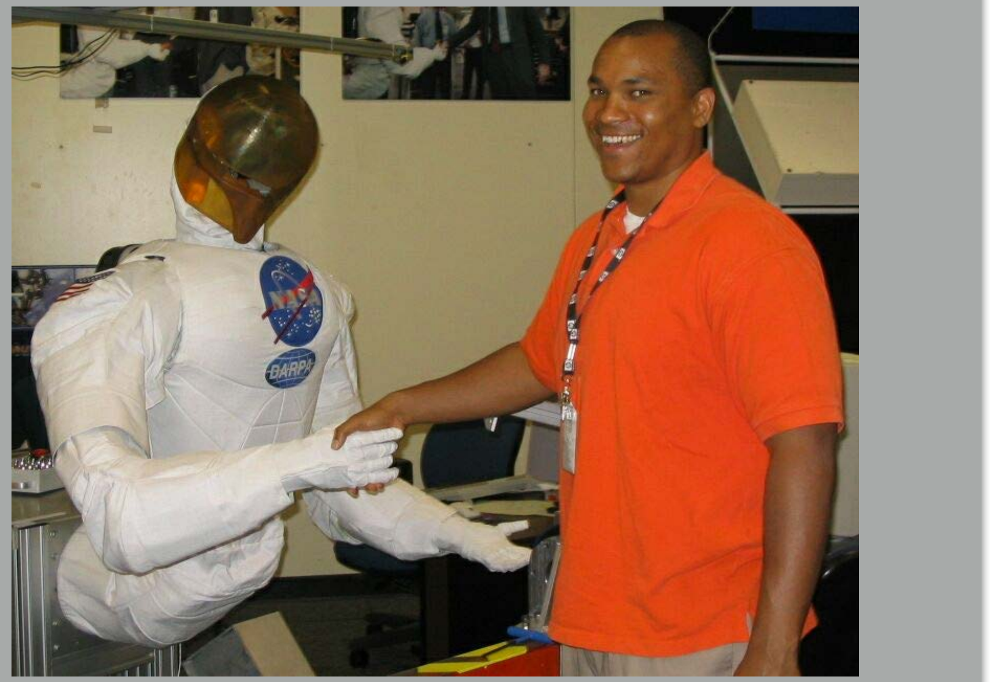
$??

NASA Robonaut



Teleoperation

(“Remote Control”)

Pick-and-Place

(“Put that there”)

Willow Garage PR2

Fetch

2001 2009 2015 2025

Time

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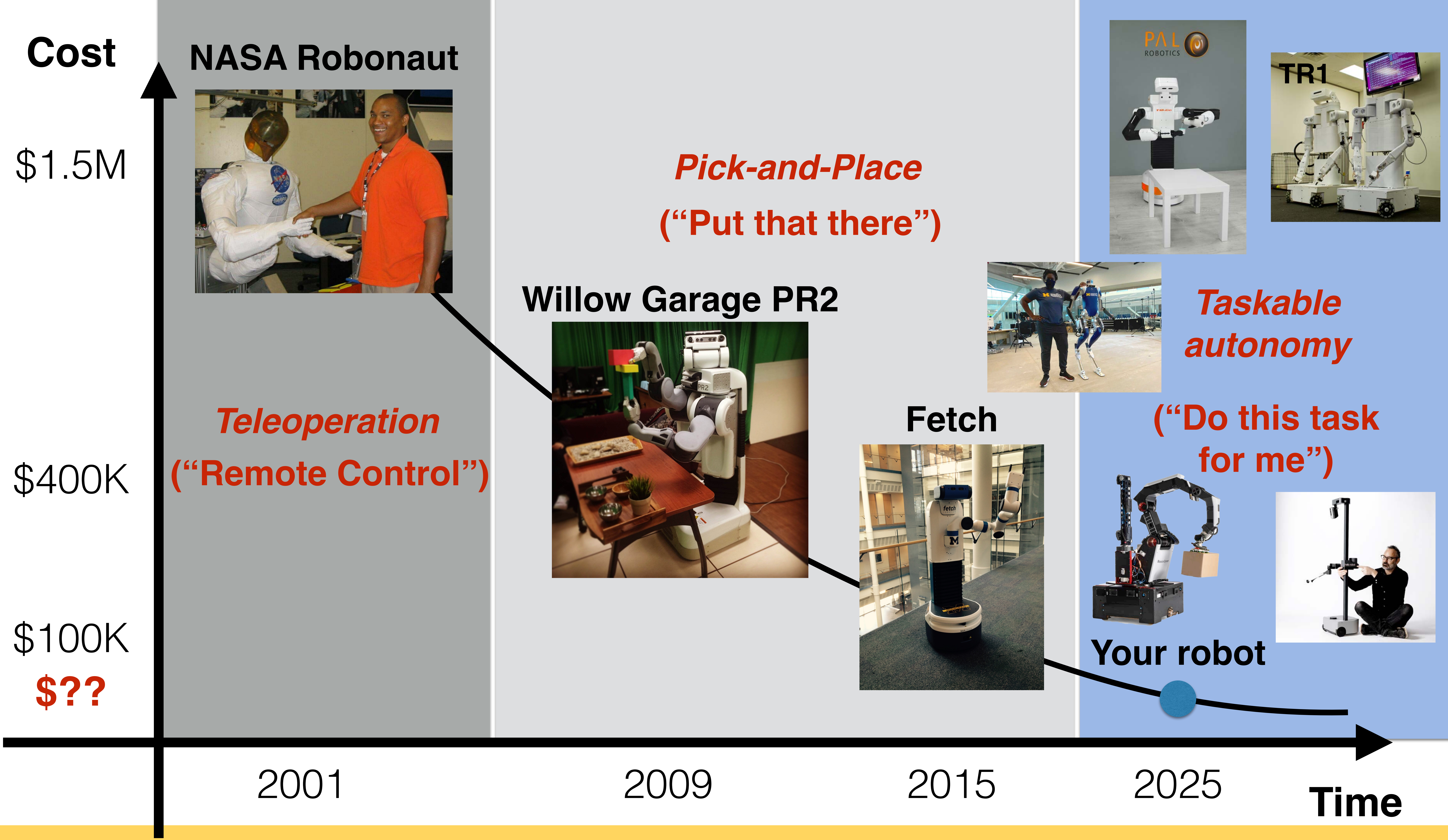

Cost

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$400K

$100K

$??

NASA Robonaut

Teleoperation

(“Remote Control”)

Willow Garage PR2

Pick-and-Place

(“Put that there”)

Fetch

Taskable autonomy

(“Do this task for me”)

TR1

Your robot

2001

2009

2015

2025

Time

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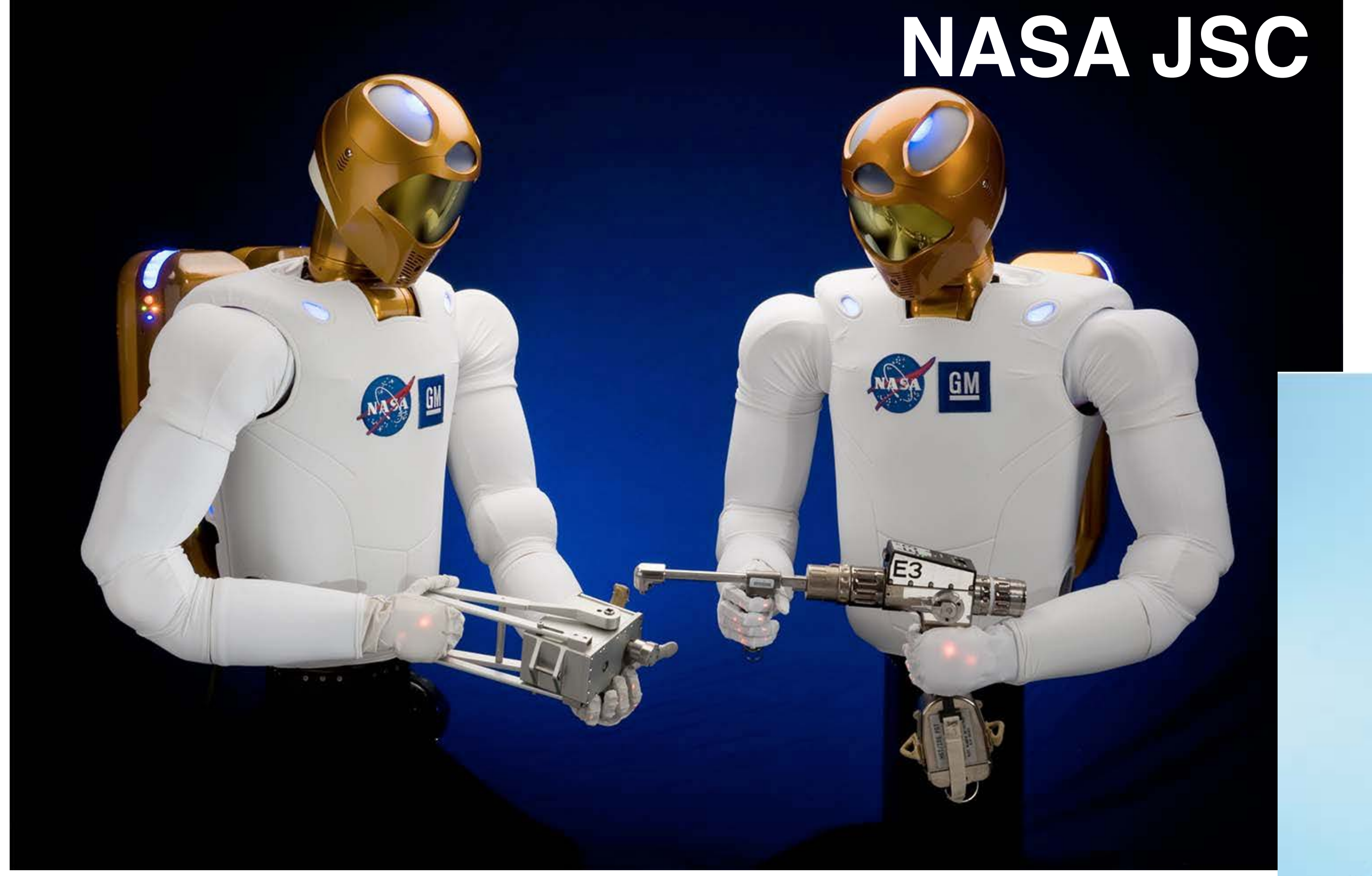
Taskable autonomy

Pick-and-Place

Teleoperation



NASA JSC

TU Munich

Dexterous Manipulation

Harvard/Wyss

TRACLabs

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Taskable autonomy

Dexterous Manipulation

Teleoperation

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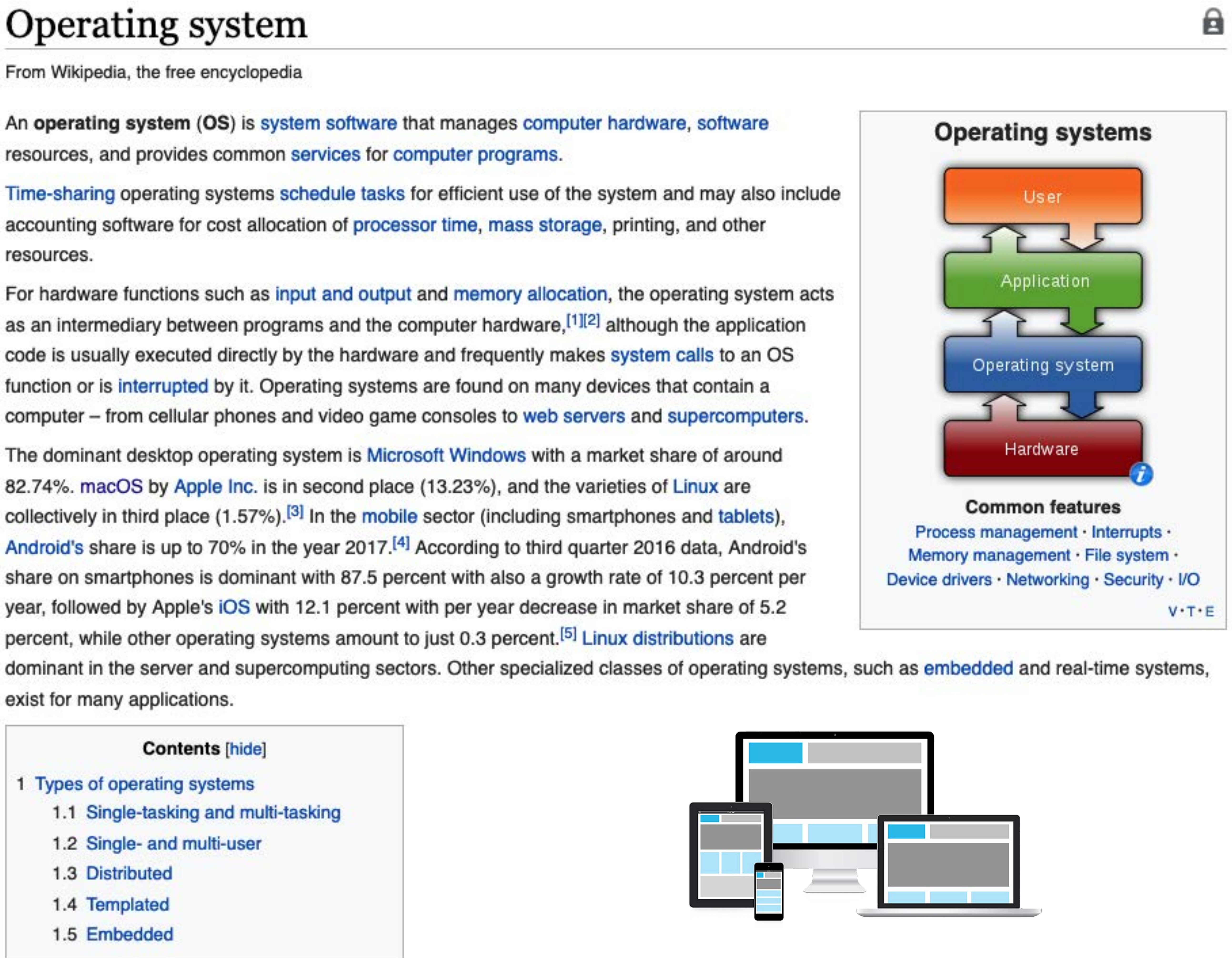
Taskable autonomy

Dexterous Manipulation

Teleoperation



Operating system

From Wikipedia, the free encyclopedia

An **operating system** (**OS**) is system software that manages computer hardware, software resources, and provides common services for computer programs.

Time-sharing operating systems schedule tasks for efficient use of the system and may also include accounting software for cost allocation of processor time, mass storage, printing, and other resources.

For hardware functions such as input and output and memory allocation, the operating system acts as an intermediary between programs and the computer hardware,[1][2] although the application code is usually executed directly by the hardware and frequently makes system calls to an OS function or is interrupted by it. Operating systems are found on many devices that contain a computer – from cellular phones and video game consoles to web servers and supercomputers.

The dominant desktop operating system is Microsoft Windows with a market share of around 82.74%. macOS by Apple Inc. is in second place (13.23%), and the varieties of Linux are collectively in third place (1.57%).[3] In the mobile sector (including smartphones and tablets), Android's share is up to 70% in the year 2017.[4] According to third quarter 2016 data, Android's share on smartphones is dominant with 87.5 percent with also a growth rate of 10.3 percent per year, followed by Apple's iOS with 12.1 percent with per year decrease in market share of 5.2 percent, while other operating systems amount to just 0.3 percent.[5] Linux distributions are dominant in the server and supercomputing sectors. Other specialized classes of operating systems, such as embedded and real-time systems, exist for many applications.

Operating systems

Common features

Process management · Interrupts · Memory management · File system · Device drivers · Networking · Security · I/O

V · T · E

Contents [hide]

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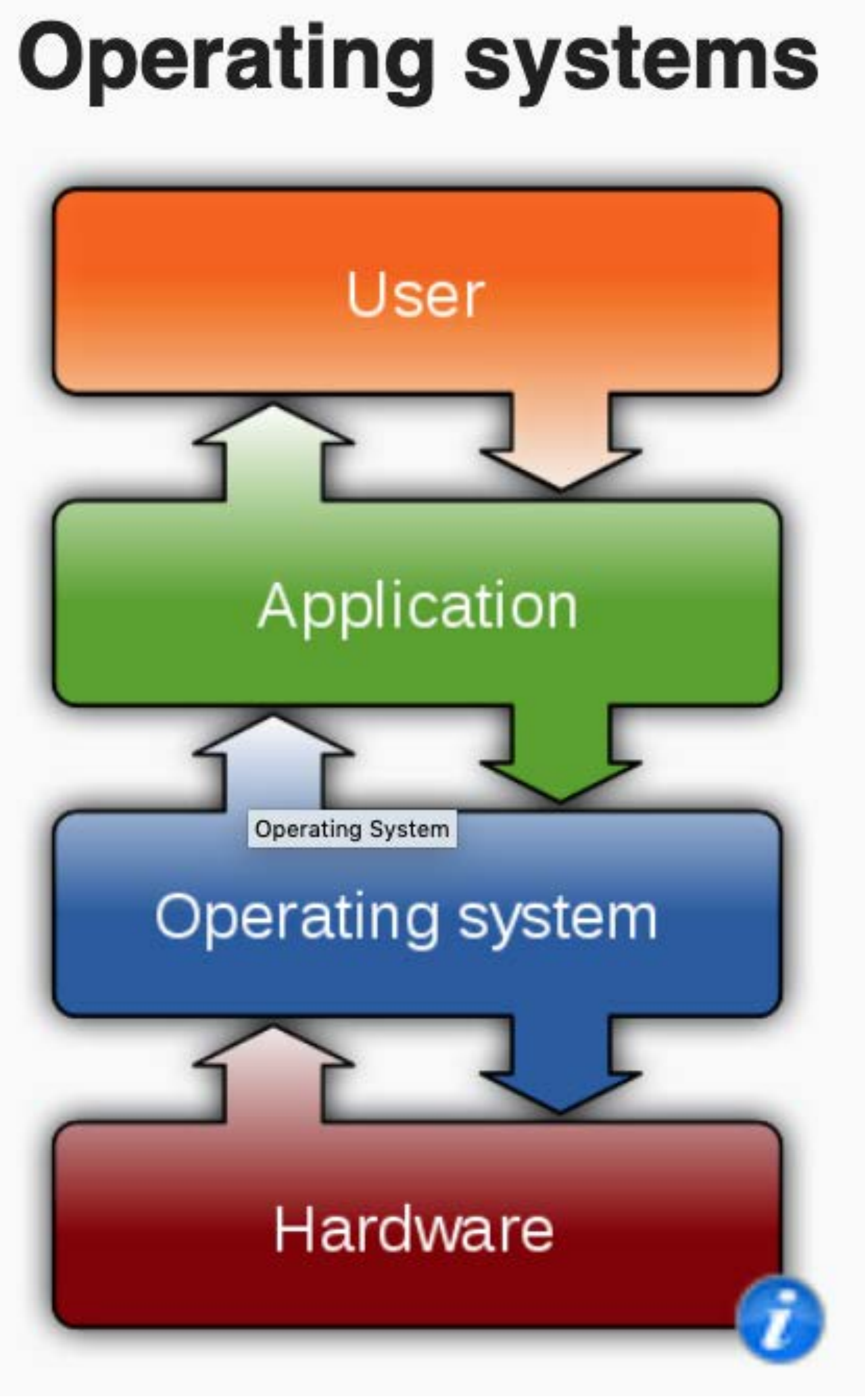
Taskable autonomy

Dexterous Manipulation

Teleoperation

An **operating system (OS)** is a special program that runs on the bare machine and hides the gory details of managing processes and devices.

- https://perldoc.perl.org/perlglossary.html#operating-system



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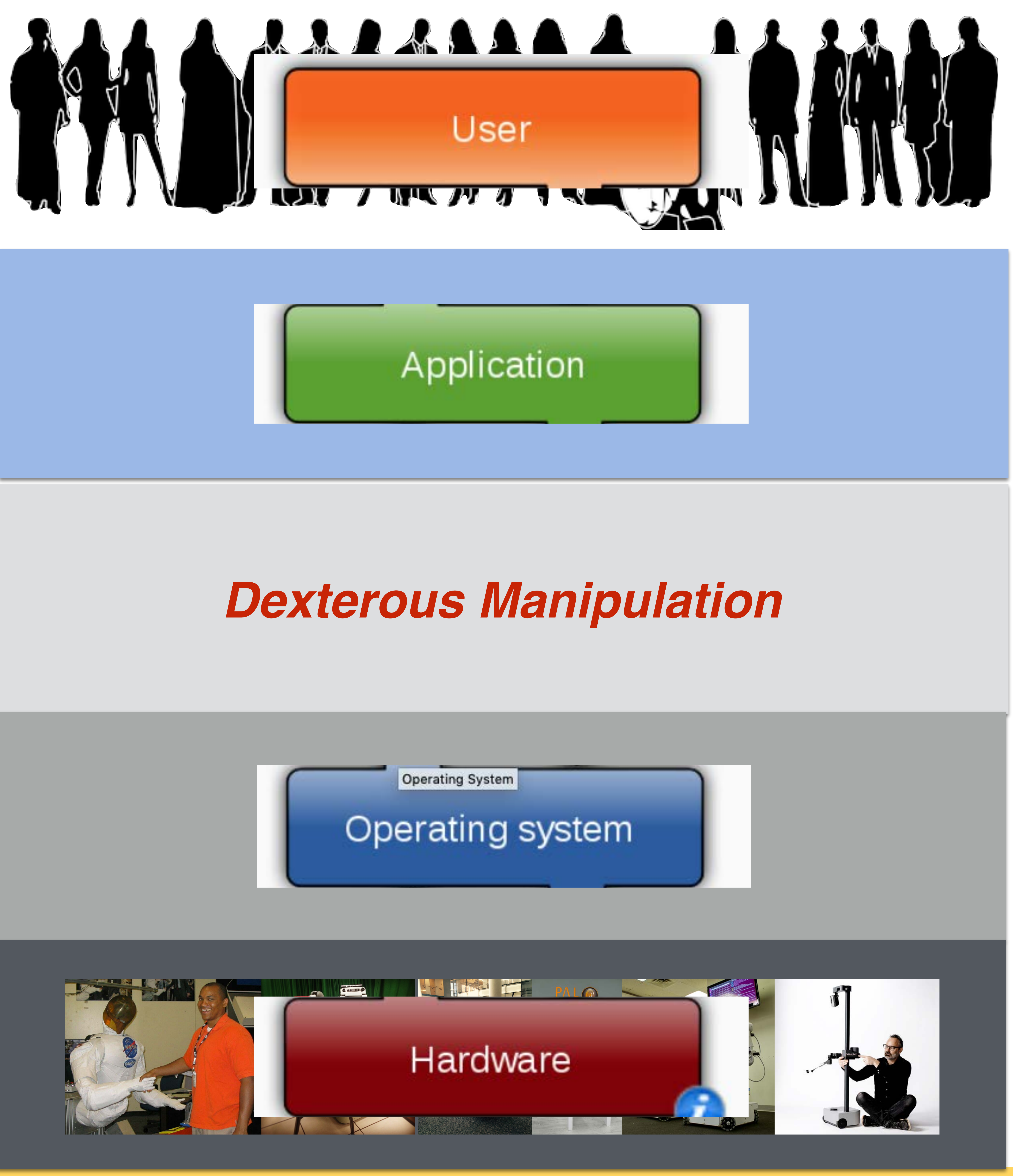

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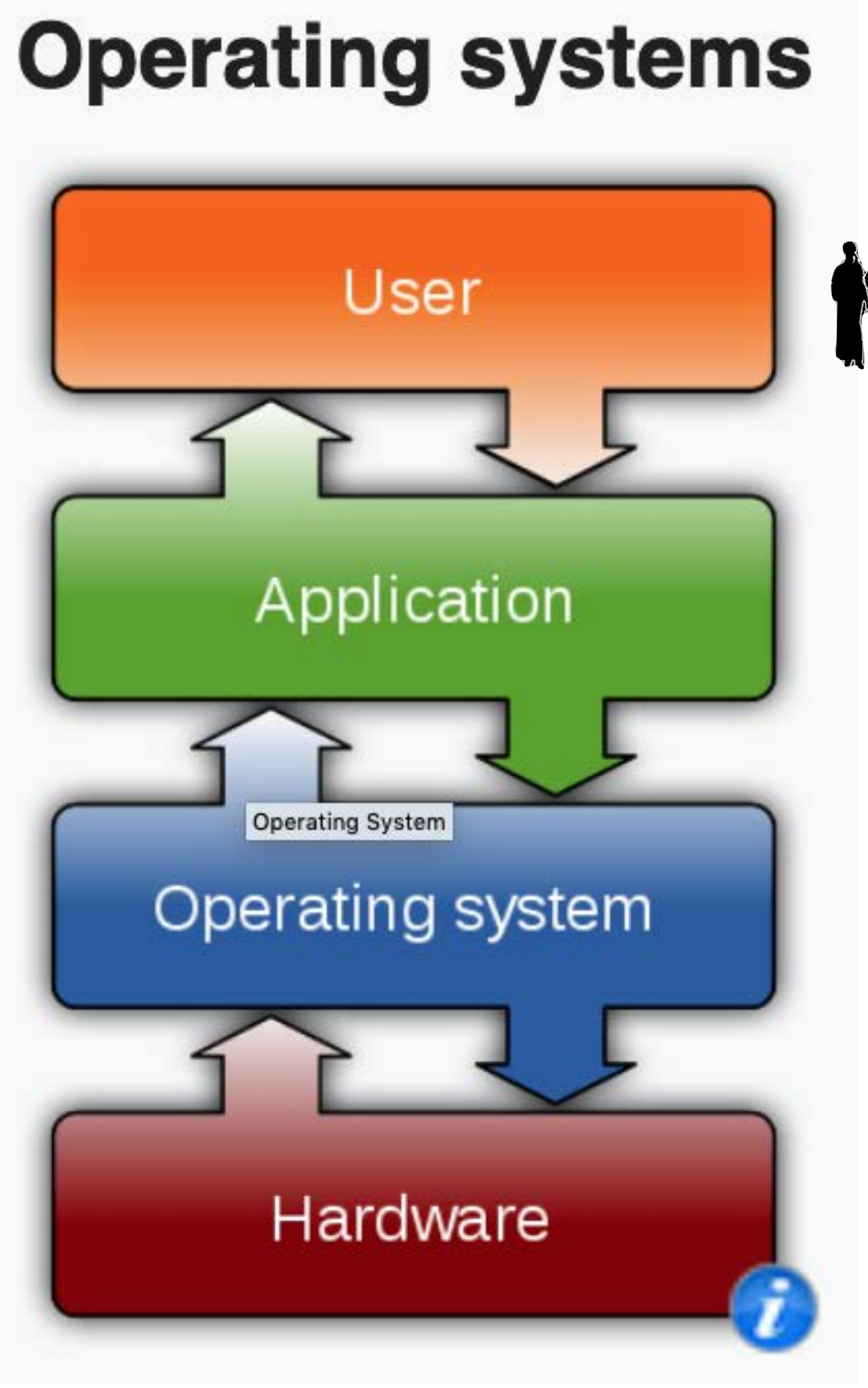

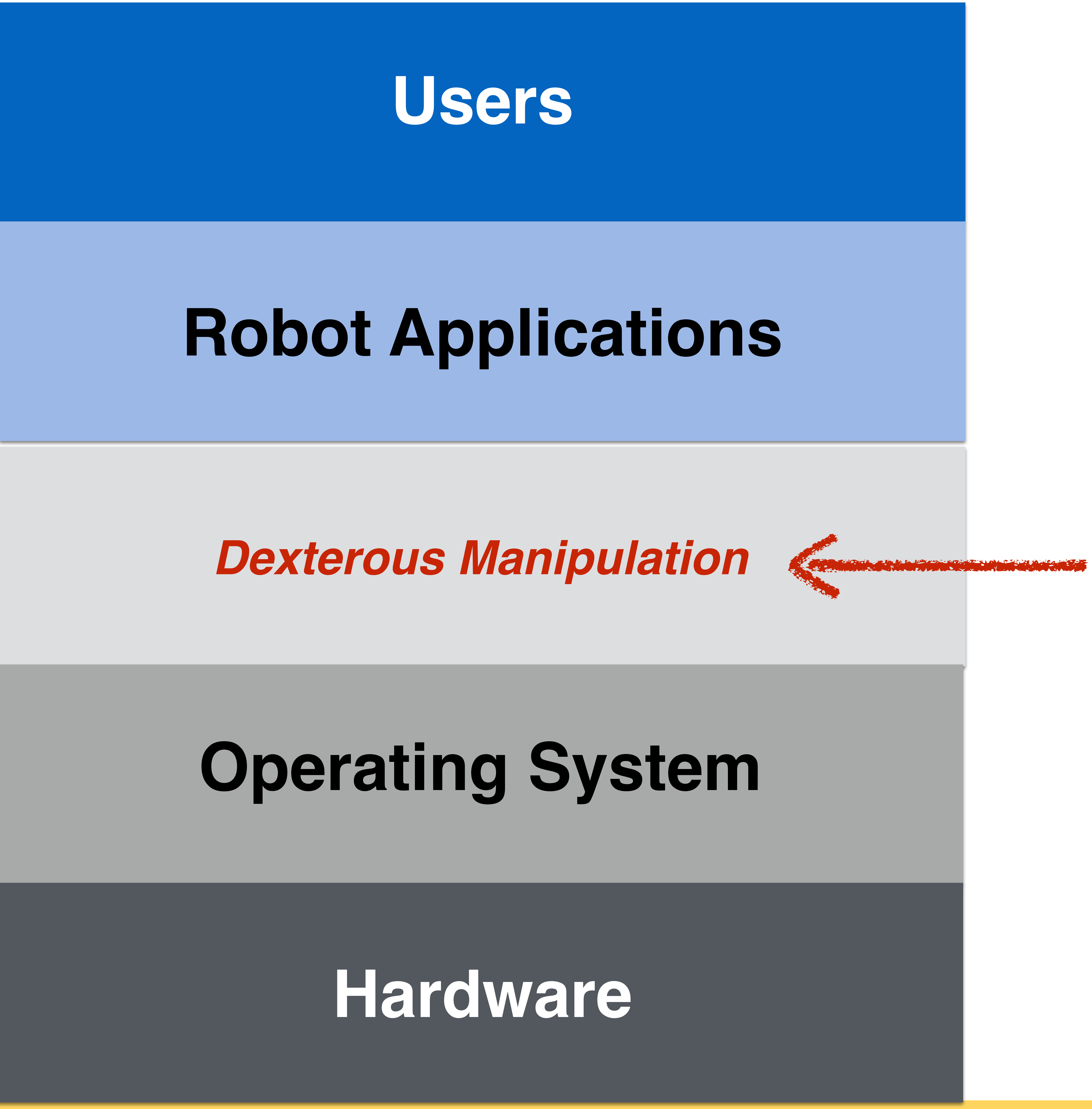

Users

Robot Applications

Dexterous Manipulation

Operating System

Hardware

Then, what is this?

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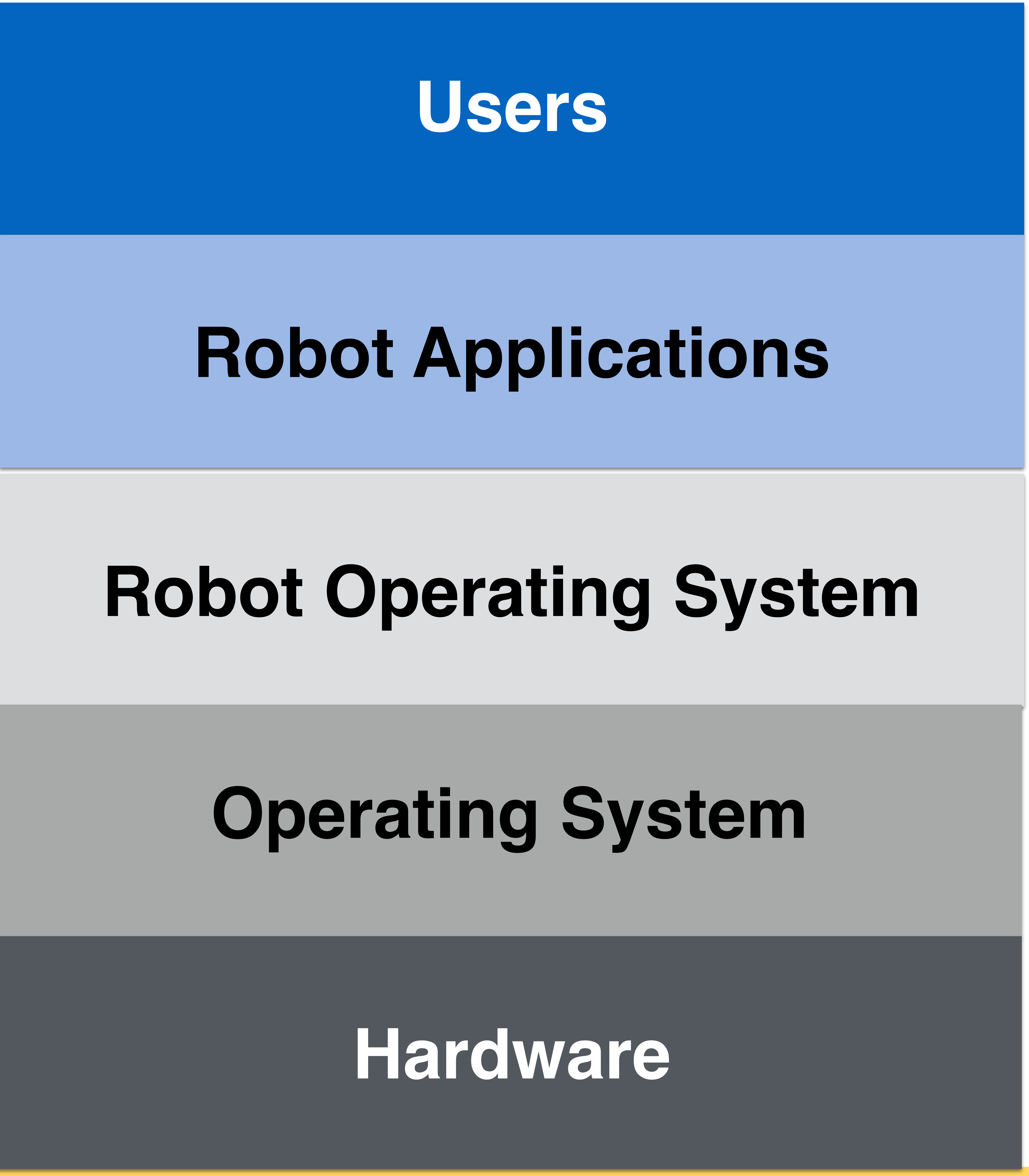

Users

Robot Applications

Robot Operating System

Operating System

Hardware

A **robot operating system (robot OS)** is a special program that runs on the operating system and hides the gory details of controlling robot devices, autonomy processes, and sensorimotor routines.

This abstraction provides a platform for robot applications to run seamlessly across a wide variety of robots capable of mobility and/or dexterous manipulation.

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Users

Robot Applications

Robot Operating System

Operating System

Hardware

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Users

Robot Applications

Robot Operating System

Operating System

Hardware

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Users

Robot Applications

Robot Operating System

LCM ROS Player YARP MOOS10

Operating System

Hardware

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Users

Robot Applications

Robot Operating System

Operating System

Hardware

LCM
ROS
Player
YARP
MOOS10
PAL ROBOTICS

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Users

Robot Applications

Then, what is this?

Robot Operating System

LCM ROS Player YARP MOOS

Operating System

Hardware

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Users

Robot Applications

Apps of the Future…
“Do this task for me”

Robot Operating System

LCM ROS Player YARP MOOS

Operating System

Hardware

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“Do this task for me”

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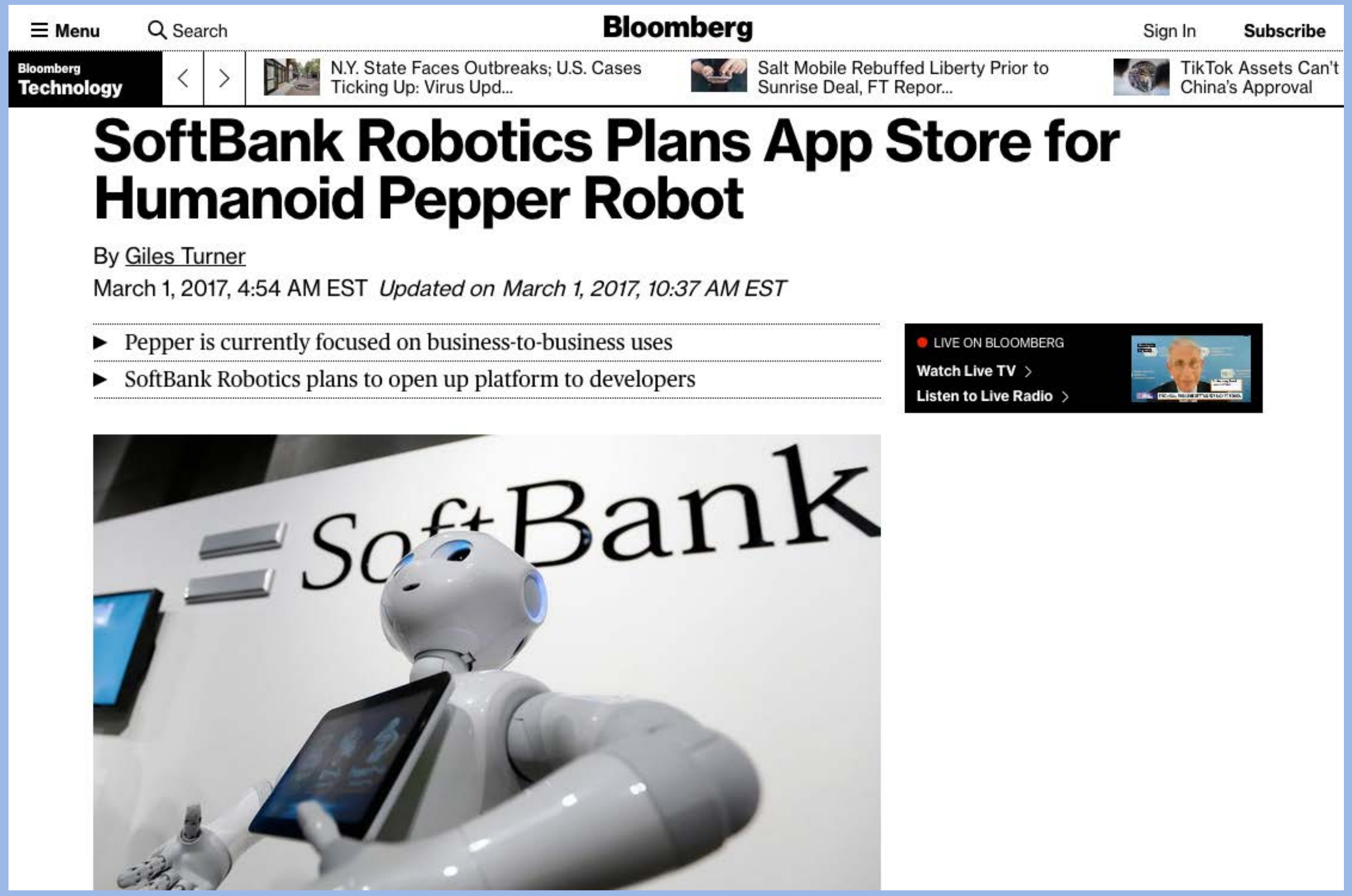
Can we make your **world programmable** ?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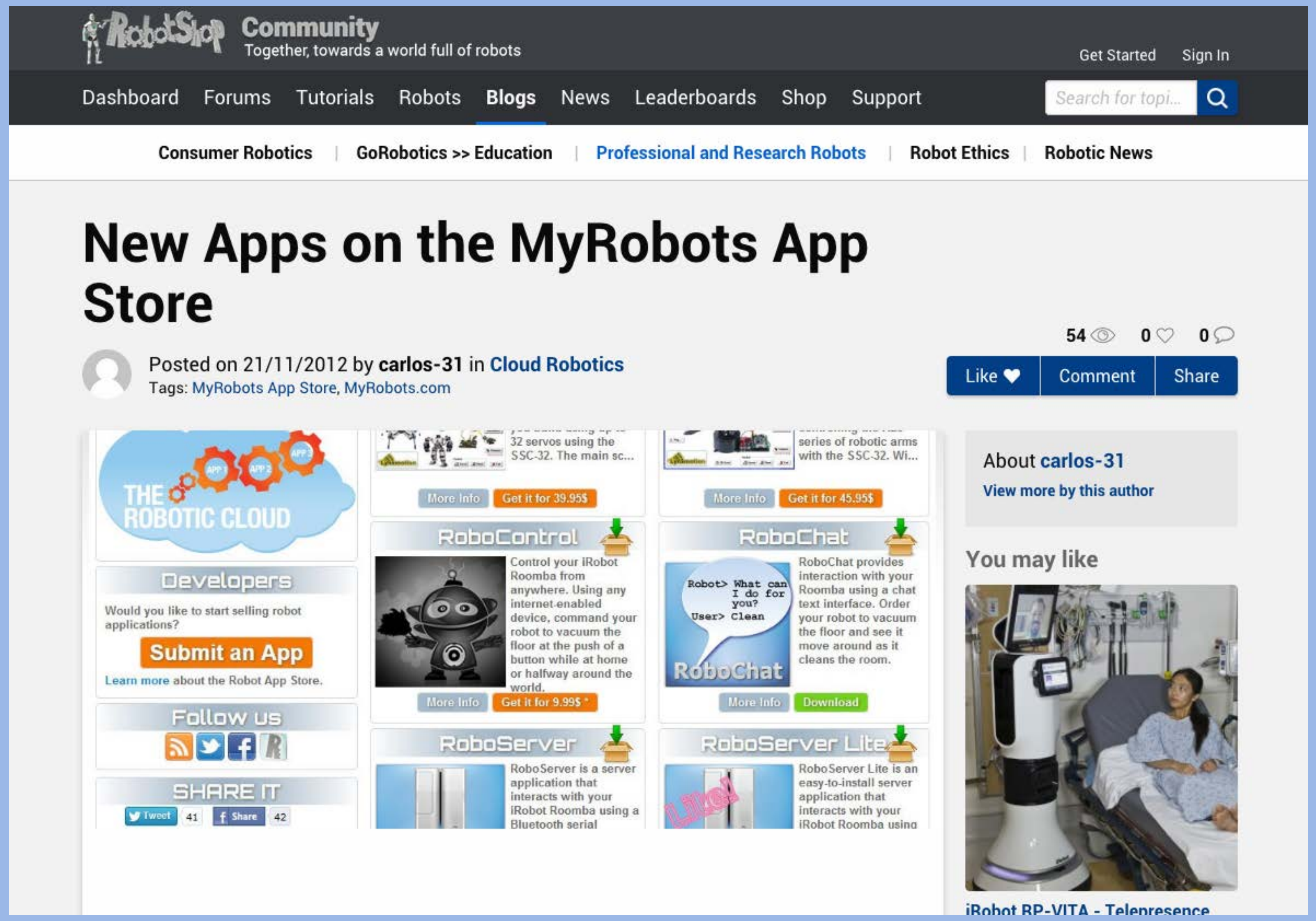
SoftBank

SoftBank Robotics Plans App Store for Humanoid Pepper Robot

By Giles Turner

March 1, 2017, 4:54 AM EST *Updated on March 1, 2017, 10:37 AM EST*

- Pepper is currently focused on business-to-business uses
- SoftBank Robotics plans to open up platform to developers



New Apps on the MyRobots App Store

Posted on 21/11/2012 by **carlos-31** in Cloud Robotics

Tags: MyRobots App Store, MyRobots.com

Would you like to start selling robot applications?

Learn more about the Robot App Store.

32 servos using the SSC-32. The main sc...

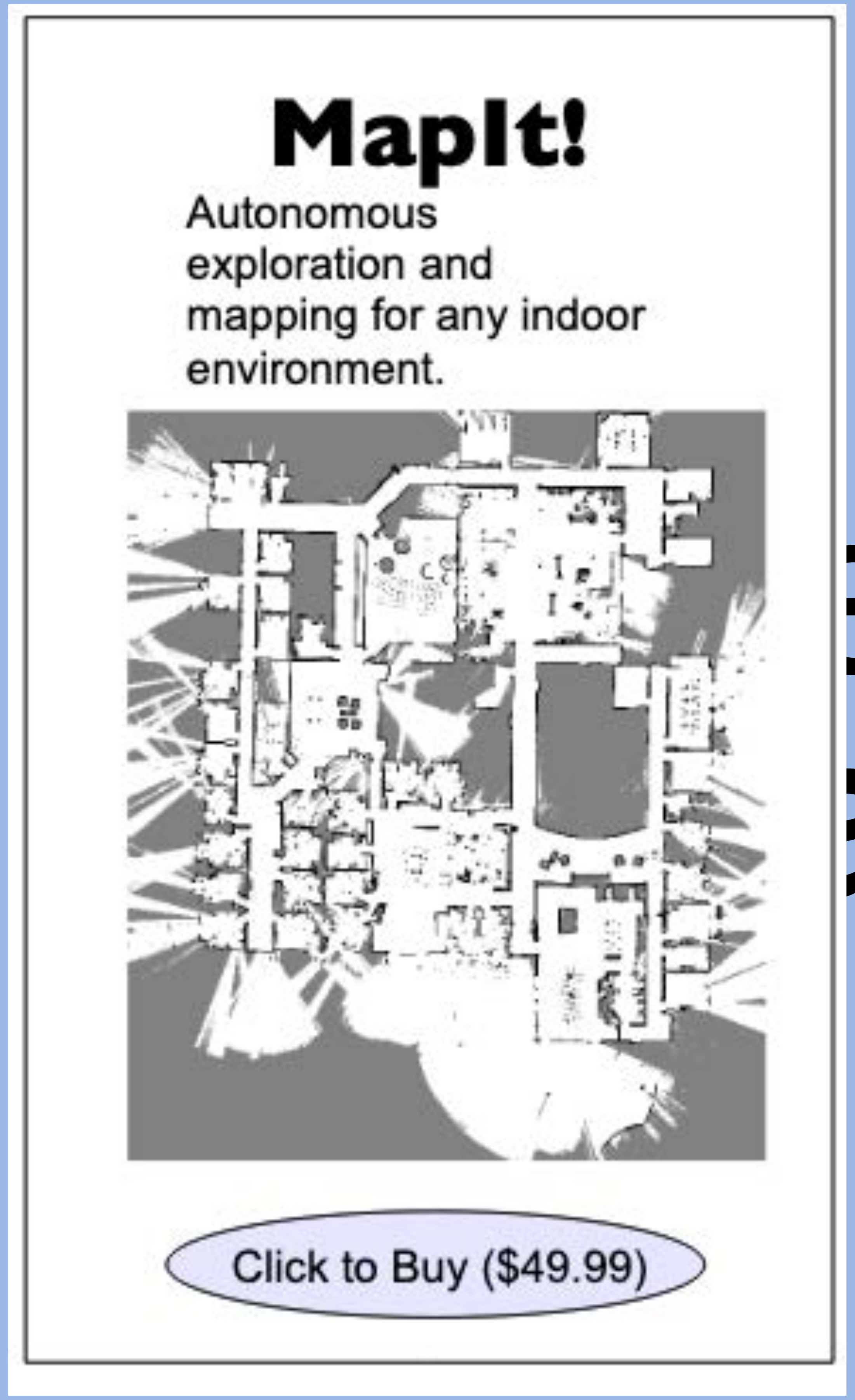
series of robotic arms with the SSC-32. Wi...

Control your iRobot Roomba from anywhere. Using any internet-enabled device, command your robot to vacuum the floor at the push of a button while at home or halfway around the world.

RoboChat provides interaction with your Roomba using a chat text interface. Order your robot to vacuum the floor and see it move around as it cleans the room.

RoboServer is a server application that interacts with your iRobot Roomba using a Bluetooth serial

RoboServer Lite is an easy-to-install server application that interacts with your iRobot Roomba using

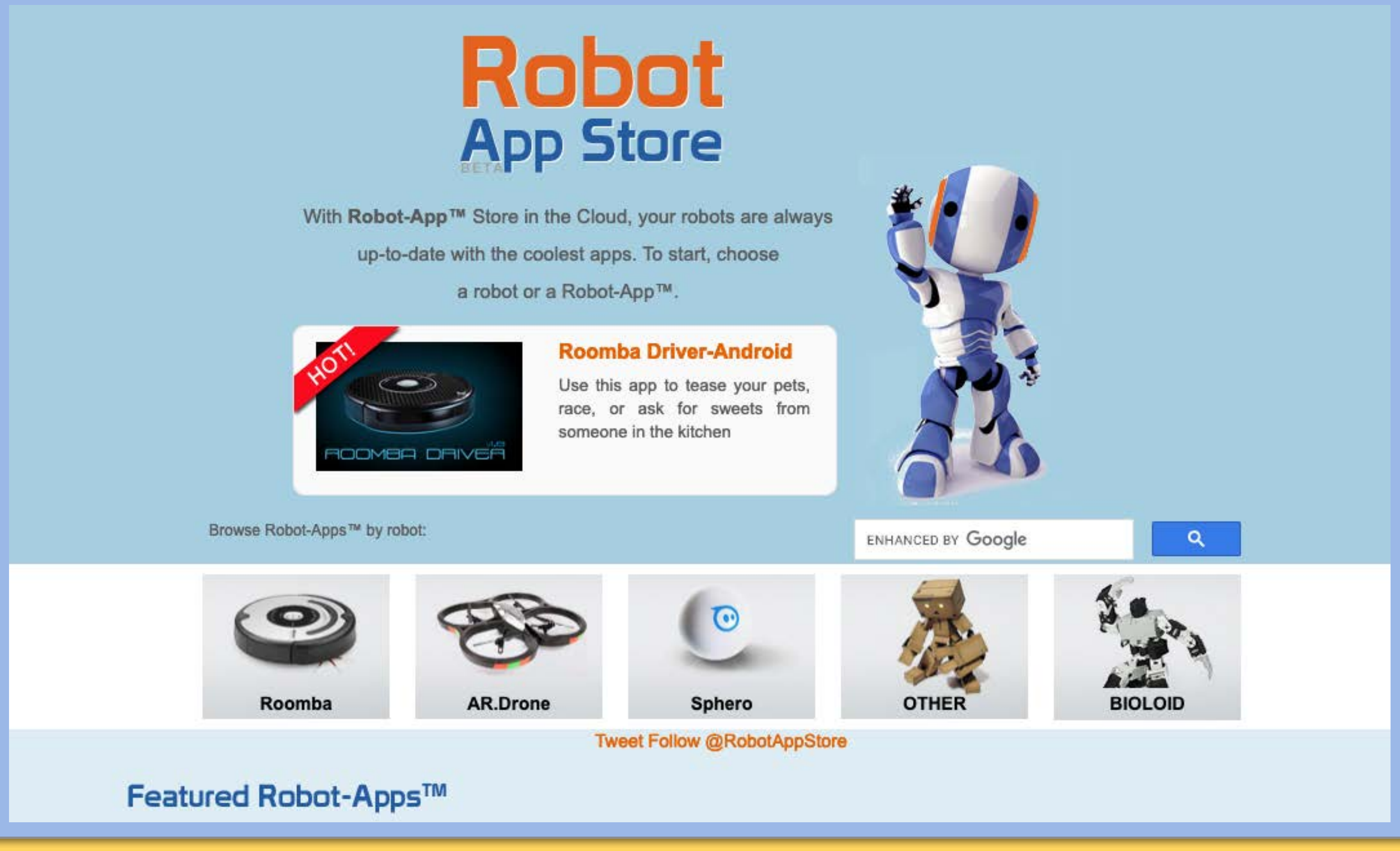


MapIt!

Autonomous exploration and mapping for any indoor environment.

Click to Buy ($49.99)

e make a
app store ?



With **Robot-App™** Store in the Cloud, your robots are always up-to-date with the coolest apps. To start, choose a robot or a Robot-App™.

Roomba Driver-Android

Use this app to tease your pets, race, or ask for sweets from someone in the kitchen

Browse Robot-Apps™ by robot:

Featured Robot-Apps™

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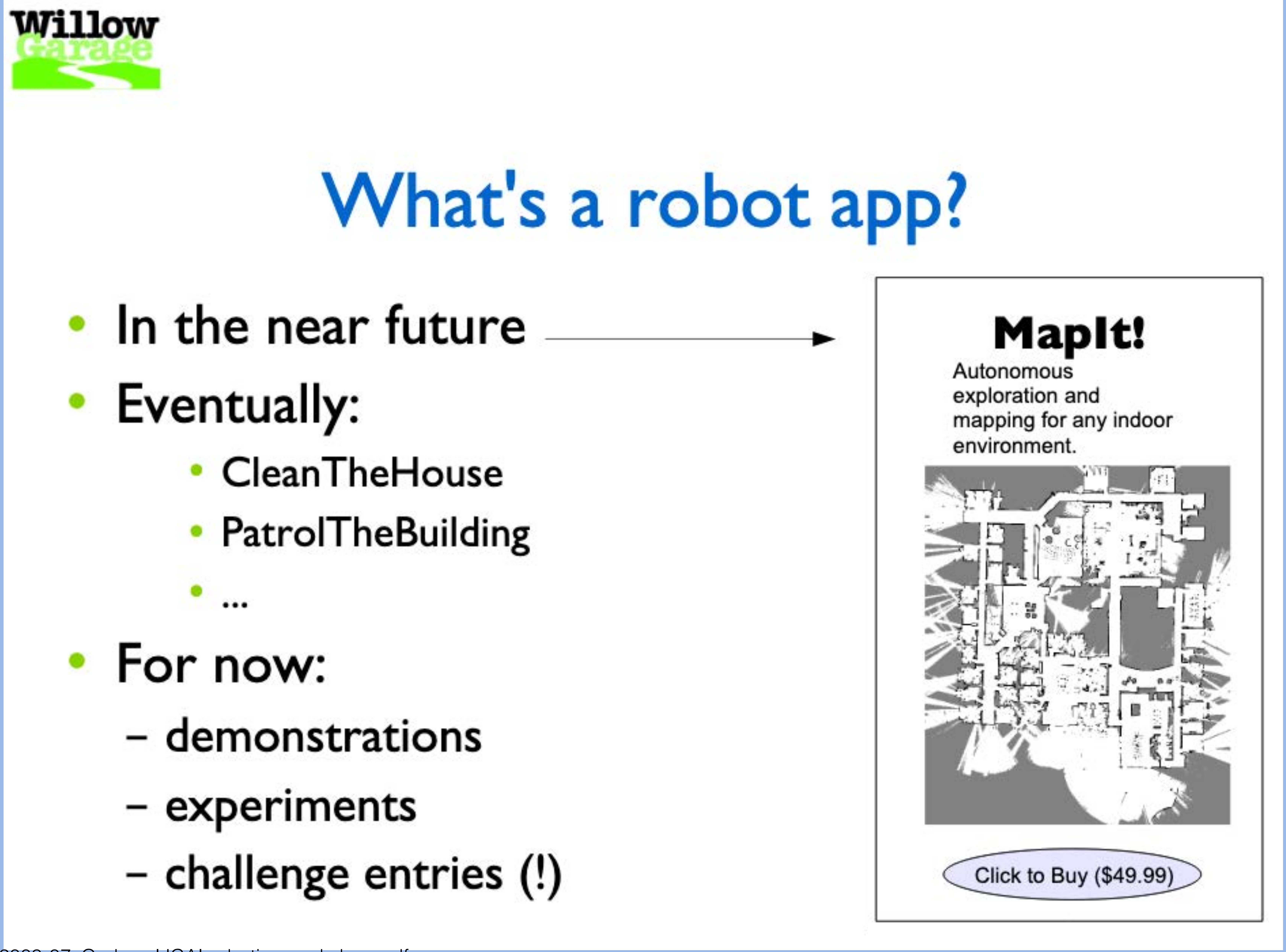

What's a robot app?

- In the near future →
- Eventually:
  - CleanTheHouse
  - PatrolTheBuilding
  - ...
- For now:
  - demonstrations
  - experiments
  - challenge entries (!)

MapIt!

Autonomous exploration and mapping for any indoor environment.

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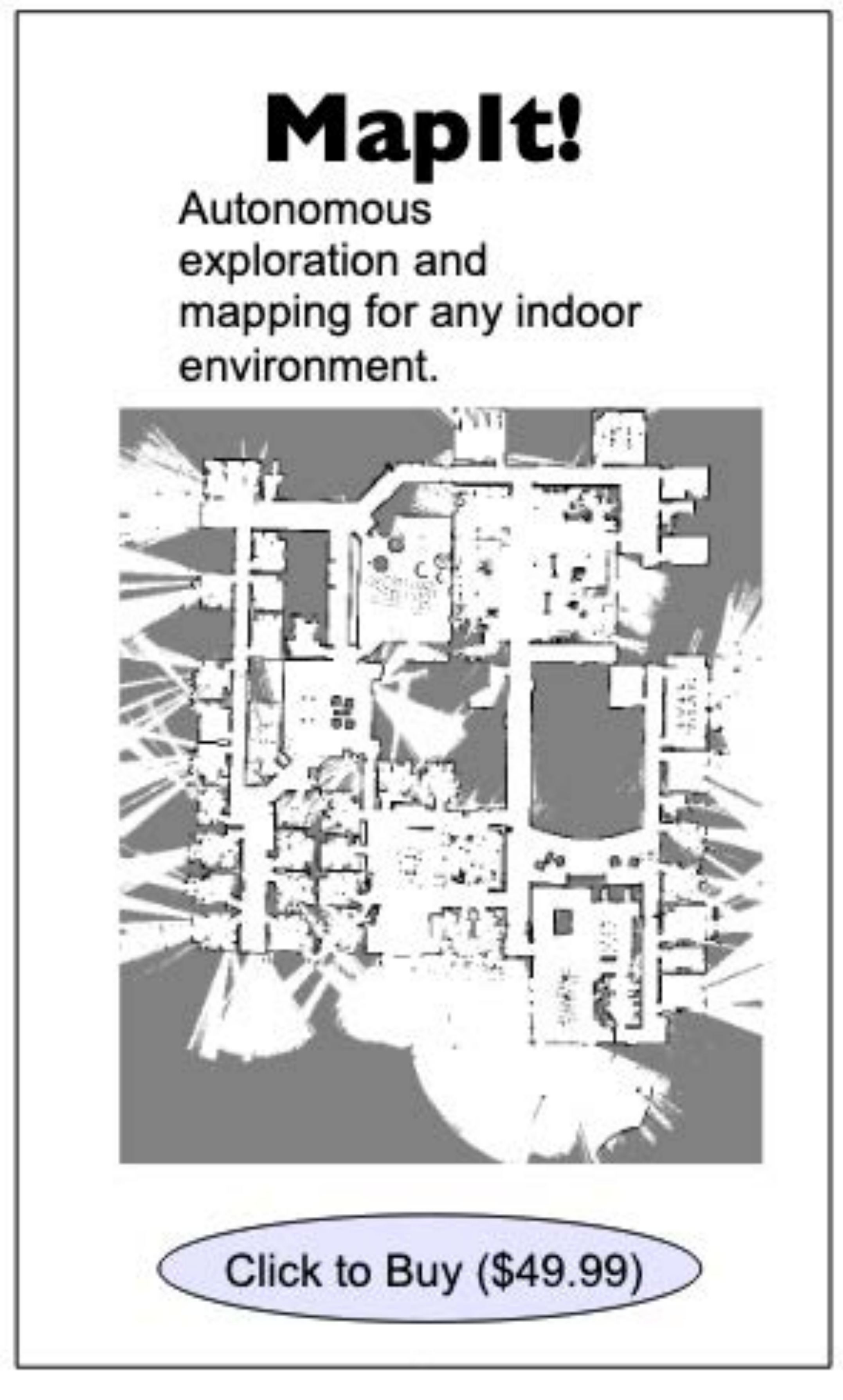
https://www.ros.org/presentations/2009-07_Gerkey_IJCAI-robotics-workshop.pdf

2009



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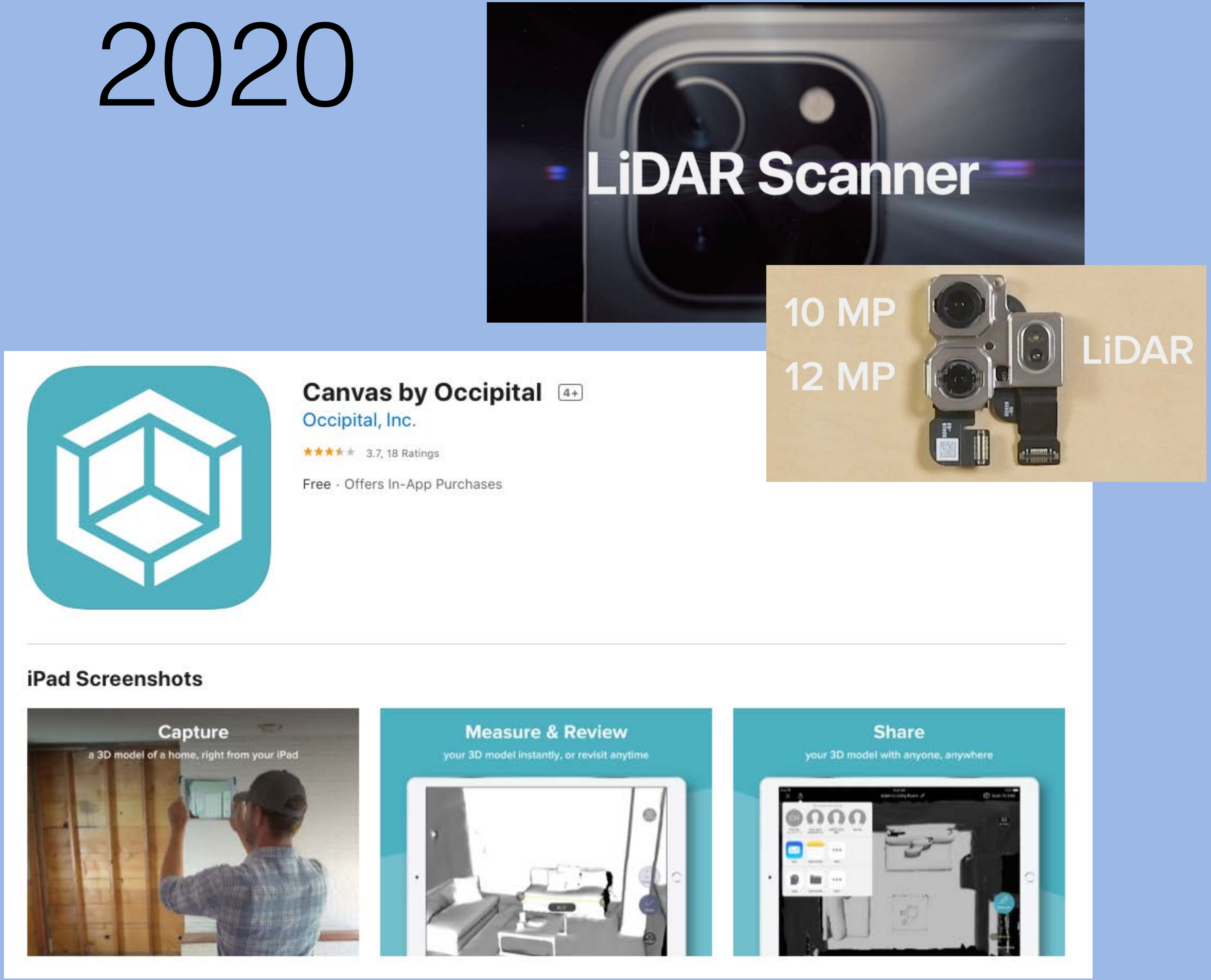
2020



Canvas by Occipital 4+

Occipital, Inc.

★★★★☆ 3.7, 18 Ratings

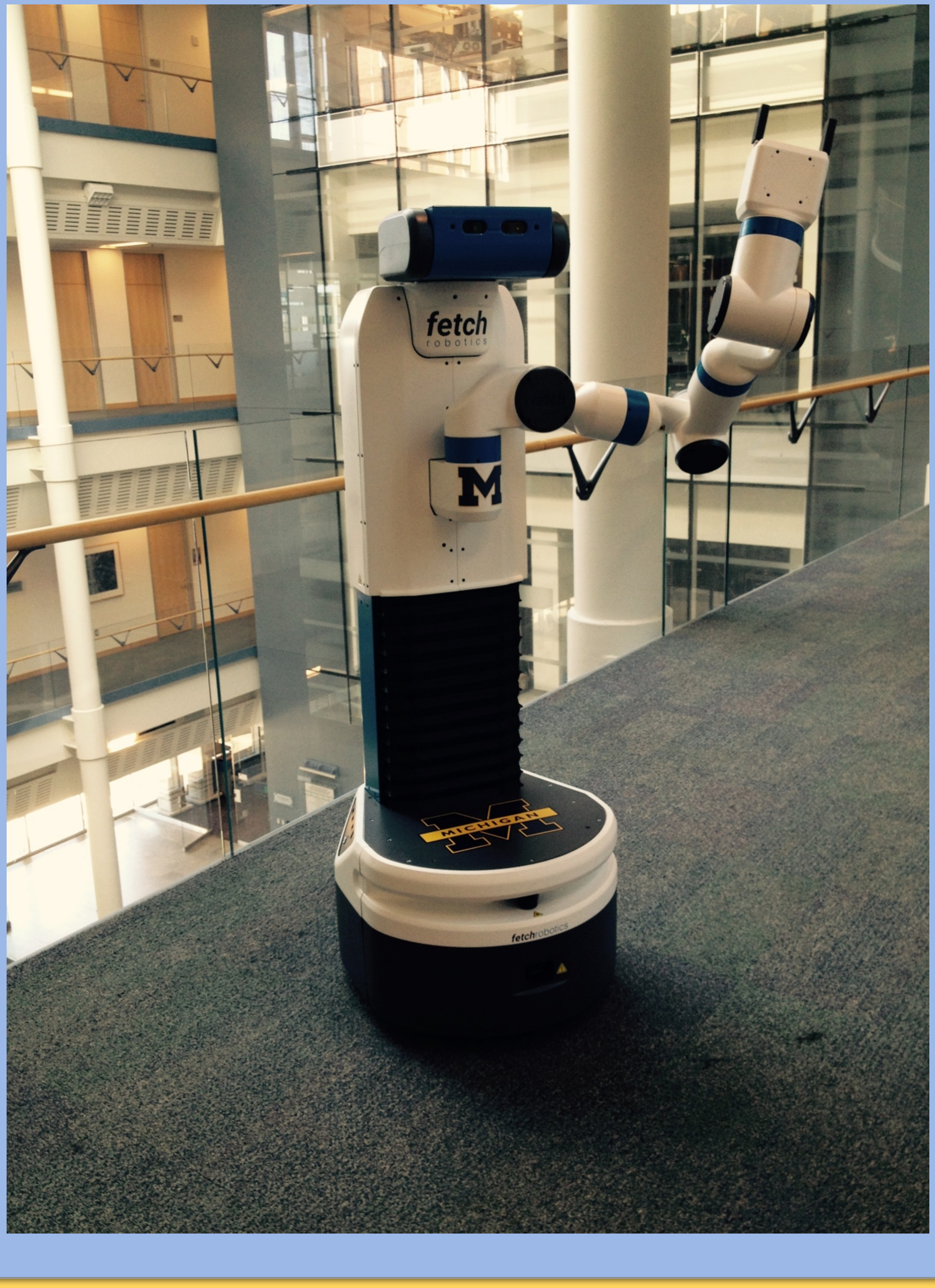
Free · Offers In-App Purchases

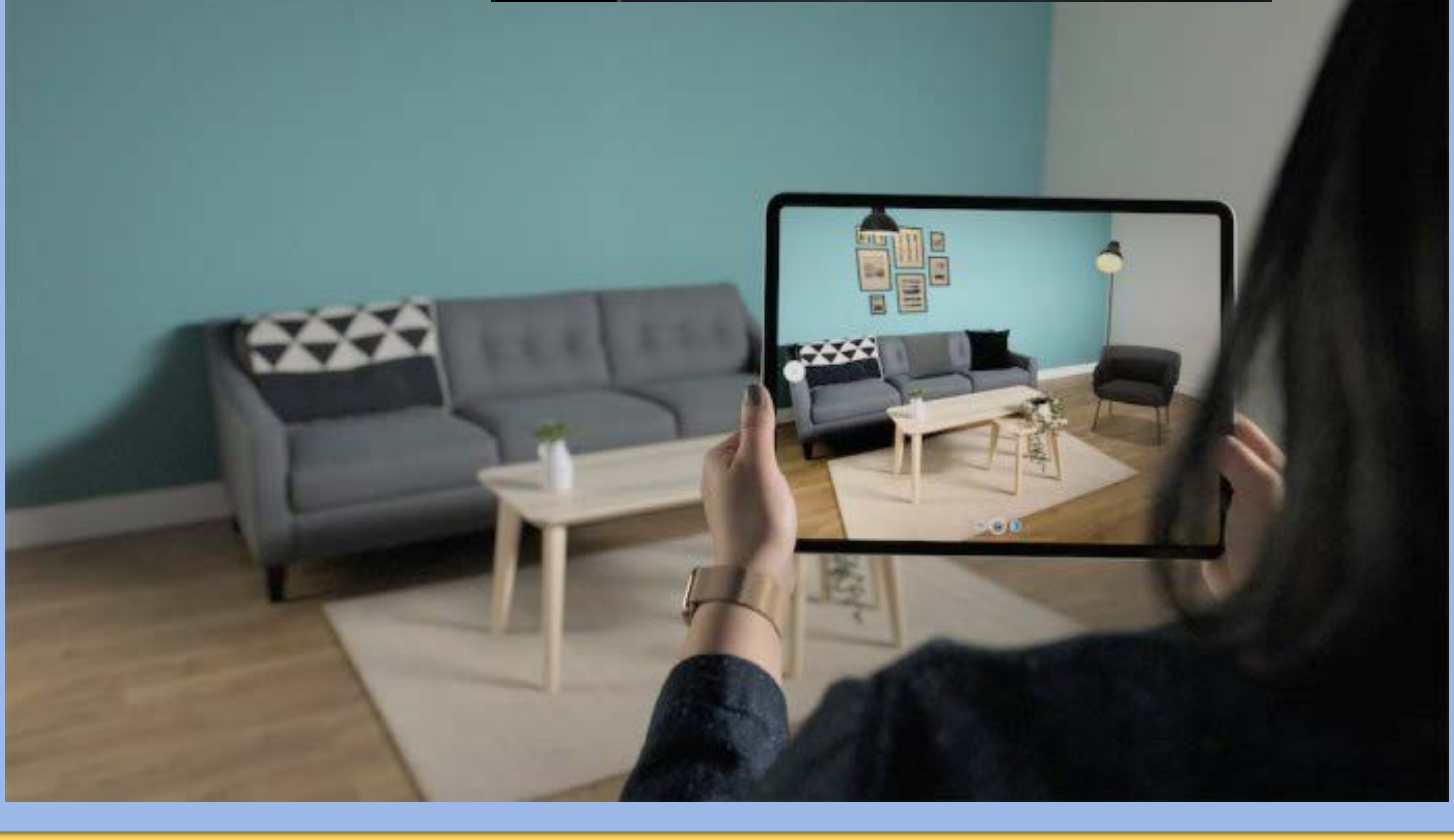
iPad Screenshots

Capture
a 3D model of a home, right from your iPad

Measure & Review
your 3D model instantly, or revisit anytime

Share
your 3D model with anyone, anywhere





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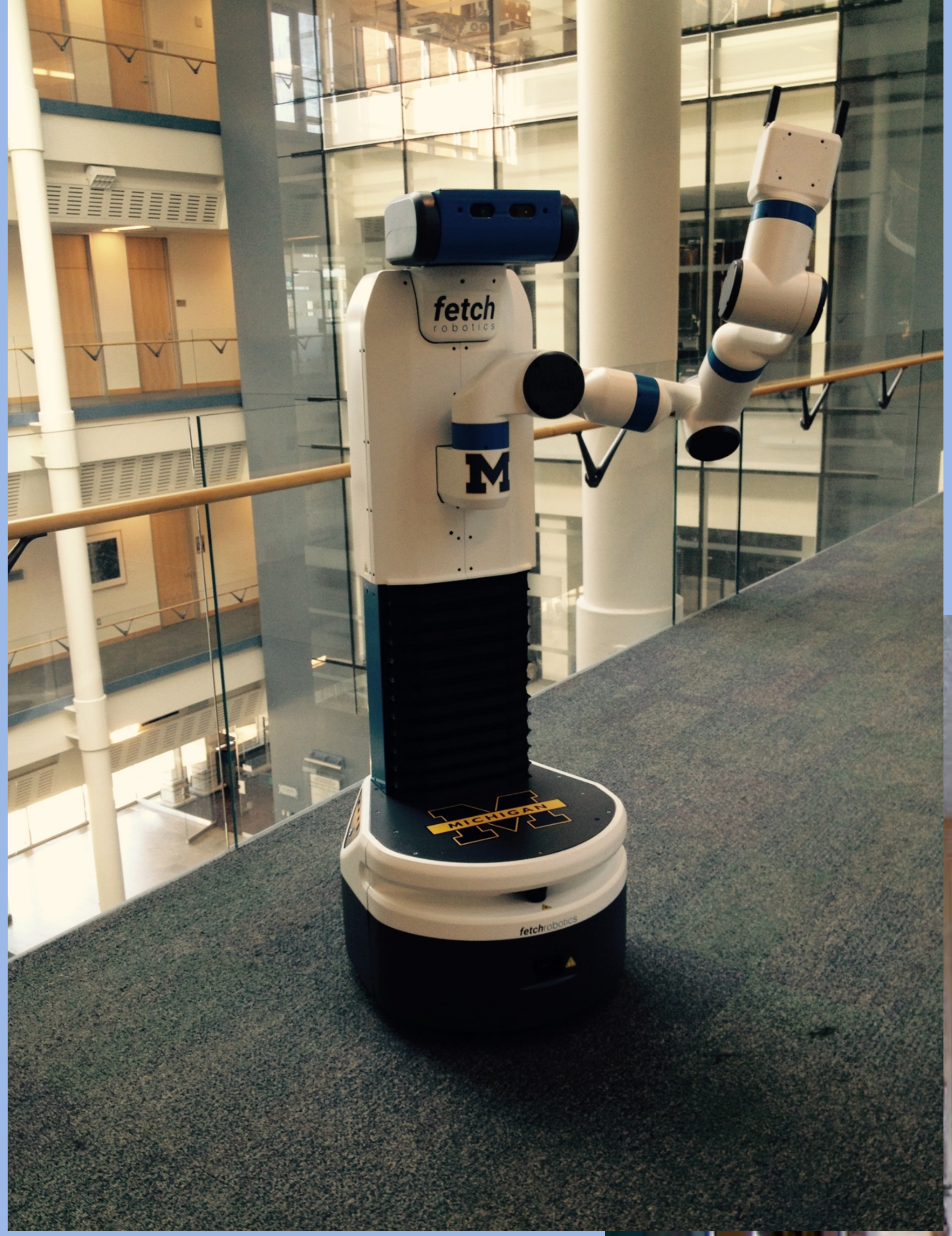
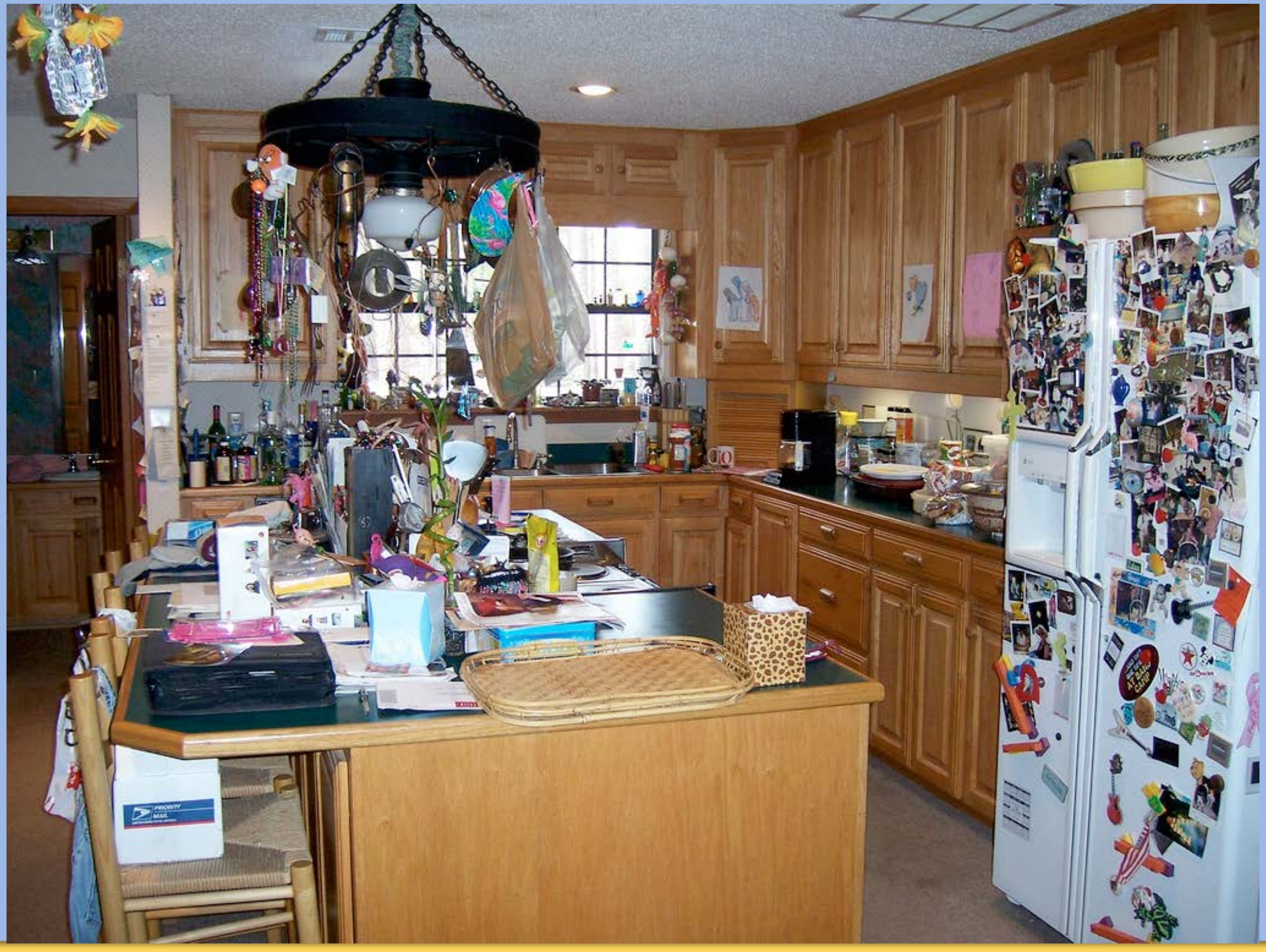


fetch
M

Use any robot x

to perform any task y

in any environment z



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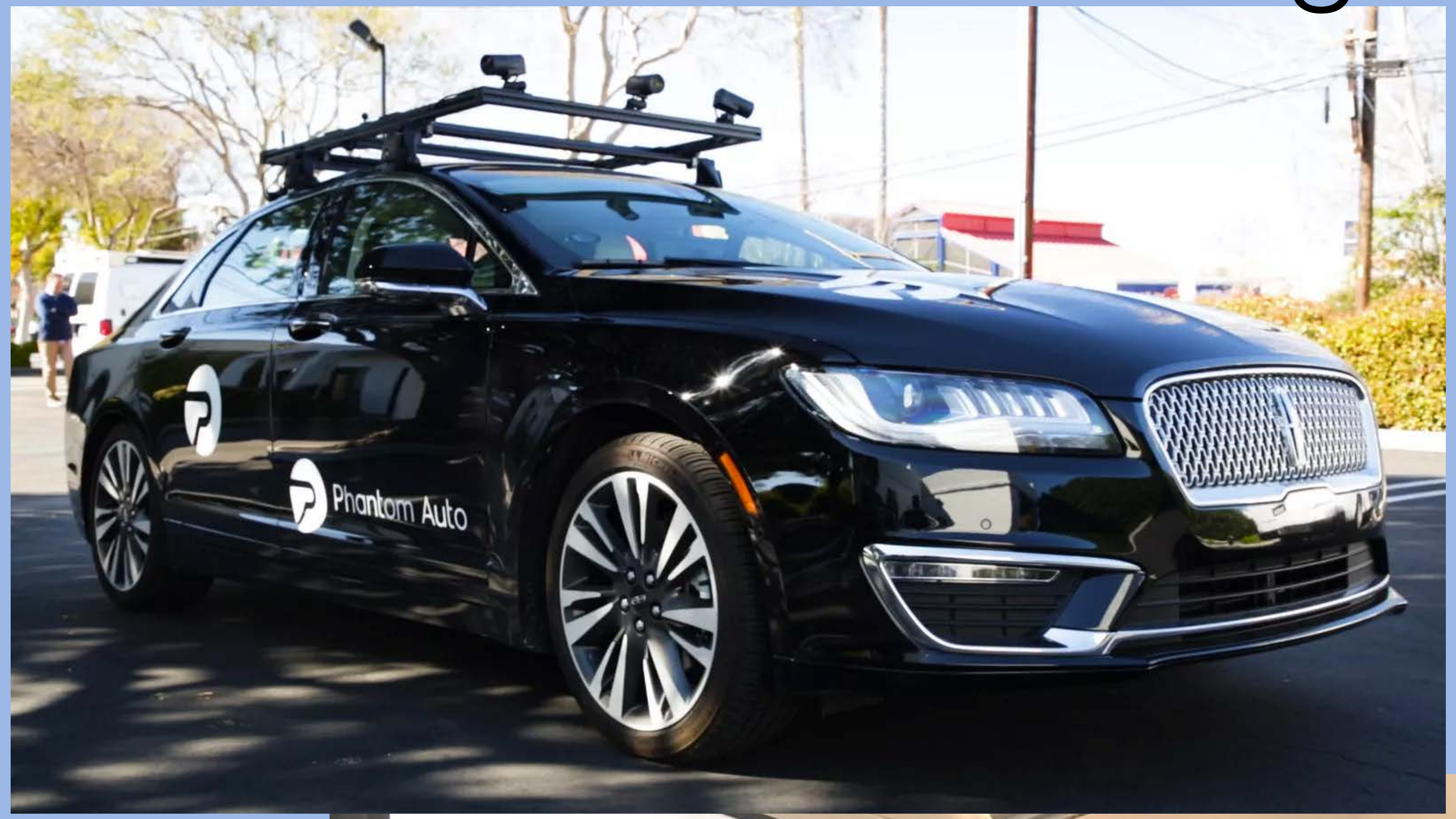
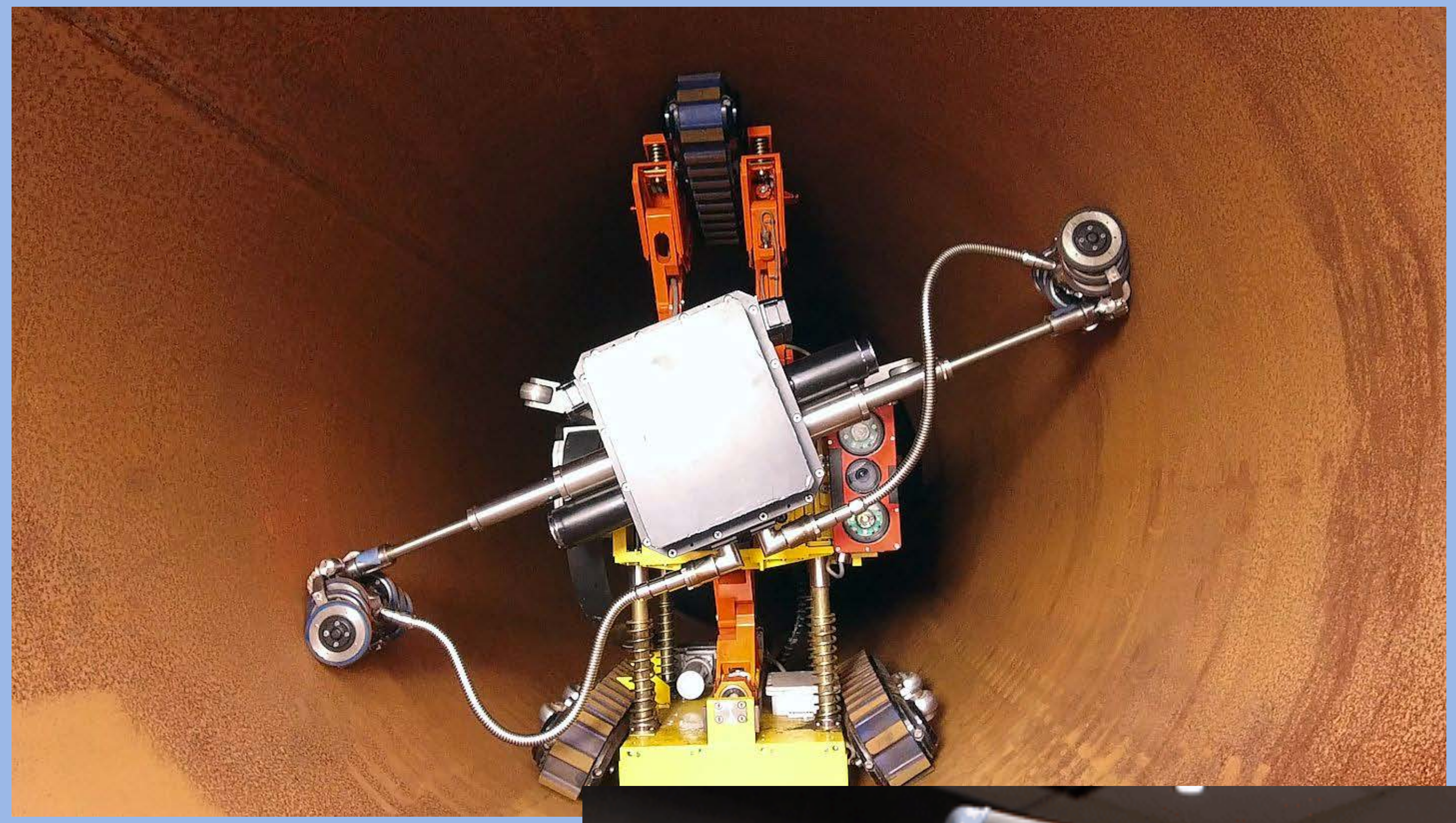
The 3Ds: Dirty, Dull, and Dangerous

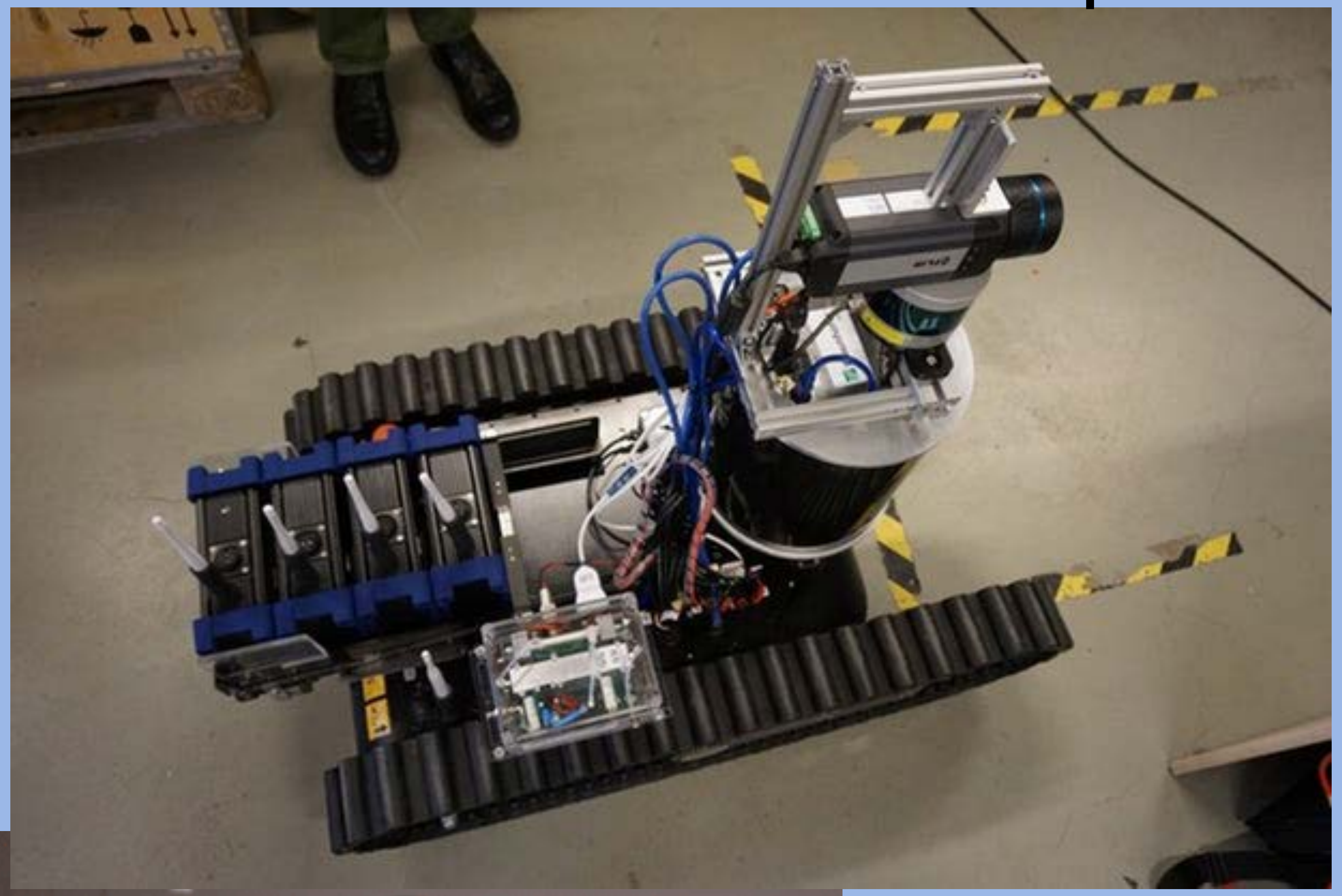
“Autonomous” Driving



Infrastructure inspection



Nuclear cleanup



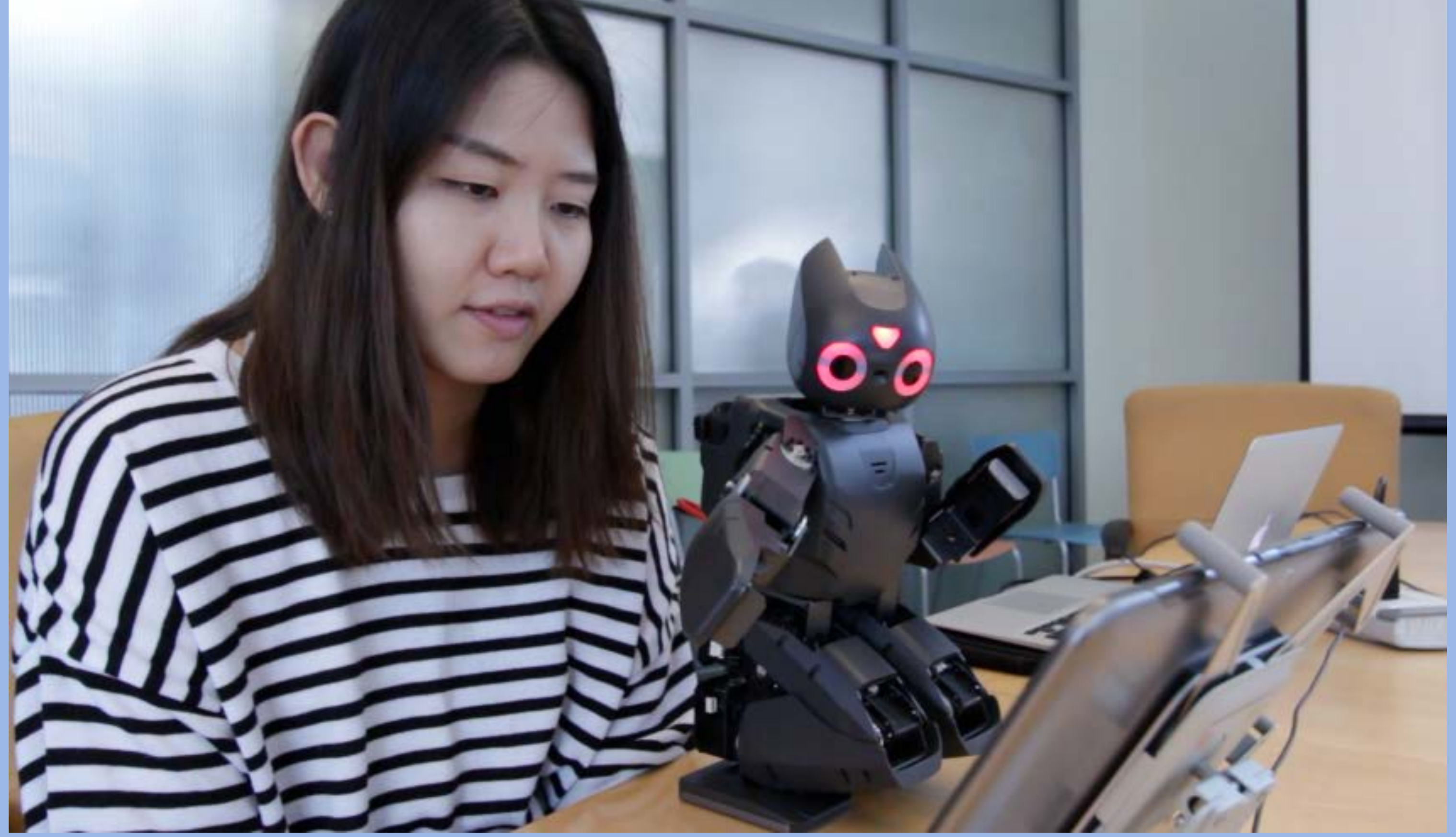
https://www.shadowrobot.com/blog/robots-saving-humans-from-dangerous-jobs/

https://techcrunch.com/2018/06/05/remote-control-driverless-car-startup-partners-with-vehicle-manufacturers/

Slide borrowed from Michigan Robotics autorob.org

Social Robotics

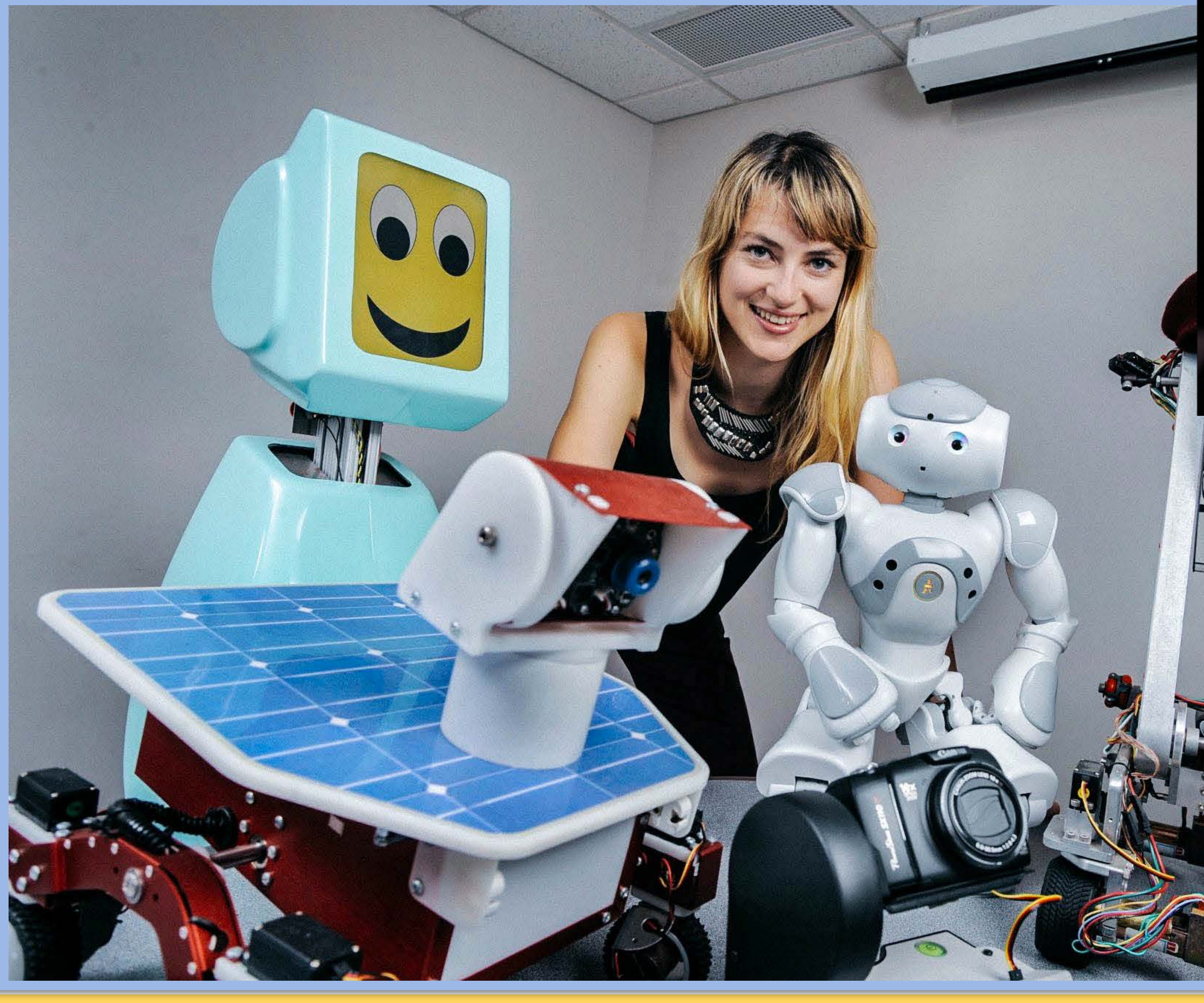
Autism treatment



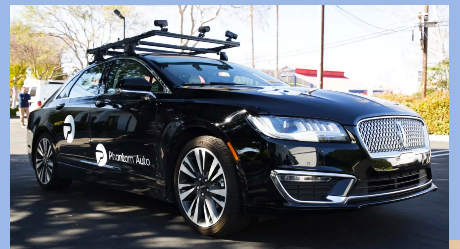
Education

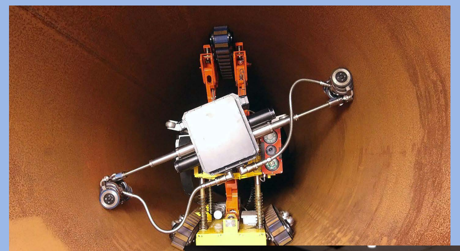
Rehabilitation

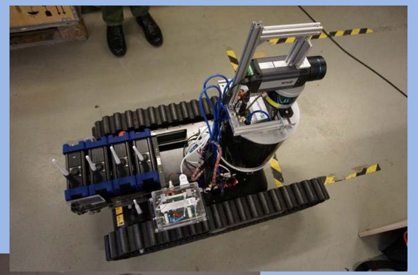
Entertainment



Elder care







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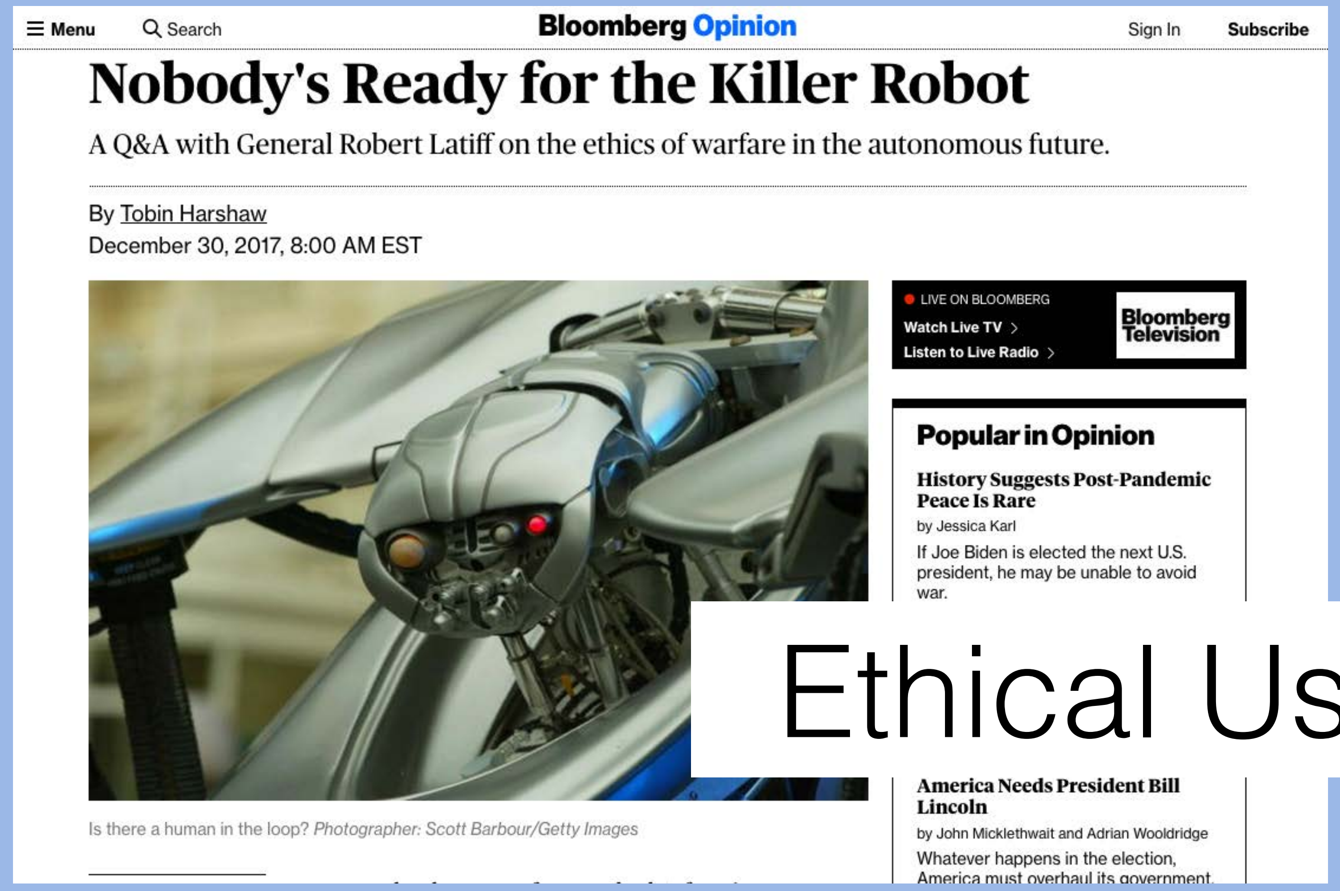
Agriculture

Exploration

Manufacturing

Security



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Nobody's Ready for the Killer Robot

A Q&A with General Robert Latiff on the ethics of warfare in the autonomous future.

By Tobin Harshaw
December 30, 2017, 8:00 AM EST

Is there a human in the loop? *Photographer: Scott Barbour/Getty Images*

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by Jessica Karl
If Joe Biden is elected the next U.S. president, he may be unable to avoid war.

America Needs President Bill Lincoln
by John Micklethwait and Adrian Wooldridge
Whatever happens in the election, America must overhaul its government

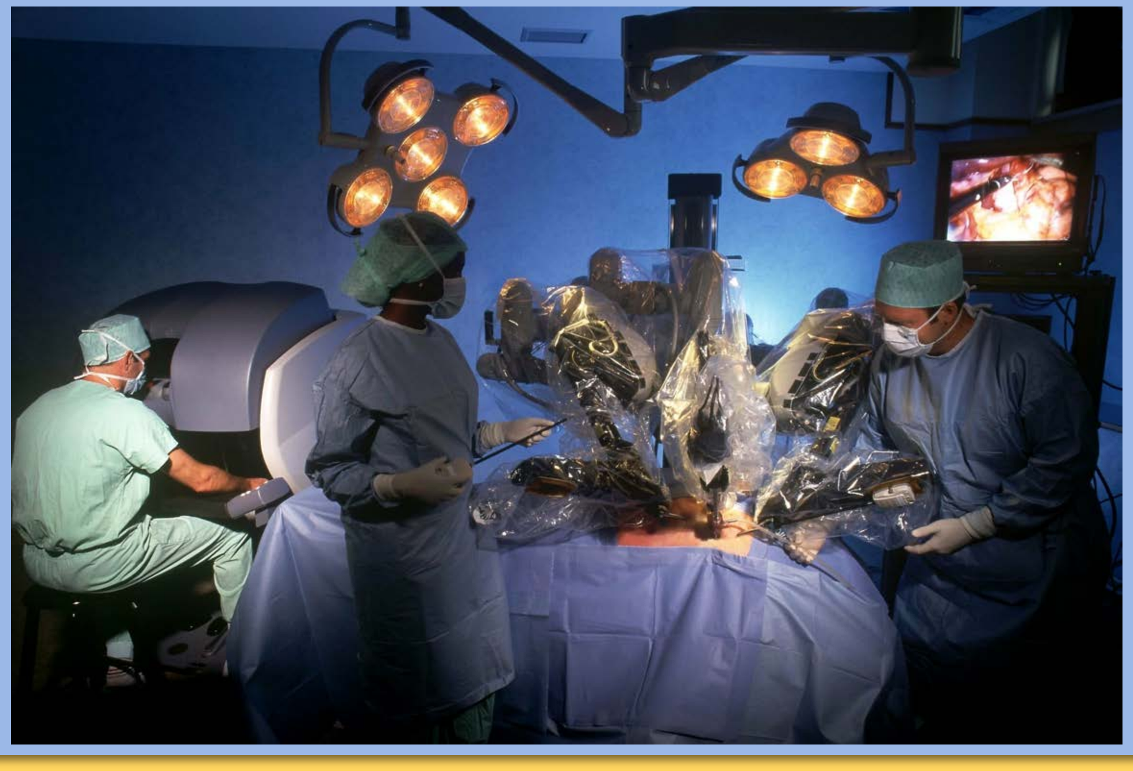
Ethical Use

Lethal Force

Social Robotics

Dirty, Dull, Dangerous

Medicine



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Users

Robot Applications

Custom applications,
Taskable autonomy research

Robot Operating System

LCM ROS Player YARP MOOS10

Operating System

Hardware

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Users

Robot Applications

Custom applications,
Taskable autonomy research

Robot Operating System

~~LCM~~ ~~ROS~~ ~~Player~~ ~~YARP~~ ~~MOOS~~10

Operating System

Hardware

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Users

Robot Applications

Custom applications,
Taskable autonomy research

Robot Operating System

Build your own Robot OS

Operating System

Hardware

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Robot Operating System

Build your own Robot OS

- Localization and Mapping
- Robot Vision
- Collision Detection
- Multi-robot Coordination

- Path Planning
- Motion Planning
- Decision Making Systems
- Task planning

- Feedback Control
- Dynamical Simulation
- Forward Kinematics
- Inverse Kinematics

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Robot Operating System

Build your own Robot OS

Localization and Mapping
Path Planning
Feedback Control
Robot Vision
Motion Planning
Dynamical Simulation
Collision Detection
Decision Making Systems
Forward Kinematics
Multi-robot Coordination
Task planning
Inverse Kinematics
Robot Middleware Architecture (via Interprocess Communication)

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Robot Operating System

Covered at **breadth** in CSCI5551

Localization and Mapping

Path Planning

Feedback Control

Robot Vision

Motion Planning

Dynamical Simulation

Collision Detection

Decision Making Systems

Forward Kinematics

Multi-robot Coordination

Task planning

Inverse Kinematics

Robot Middleware Architecture (via Interprocess Communication)

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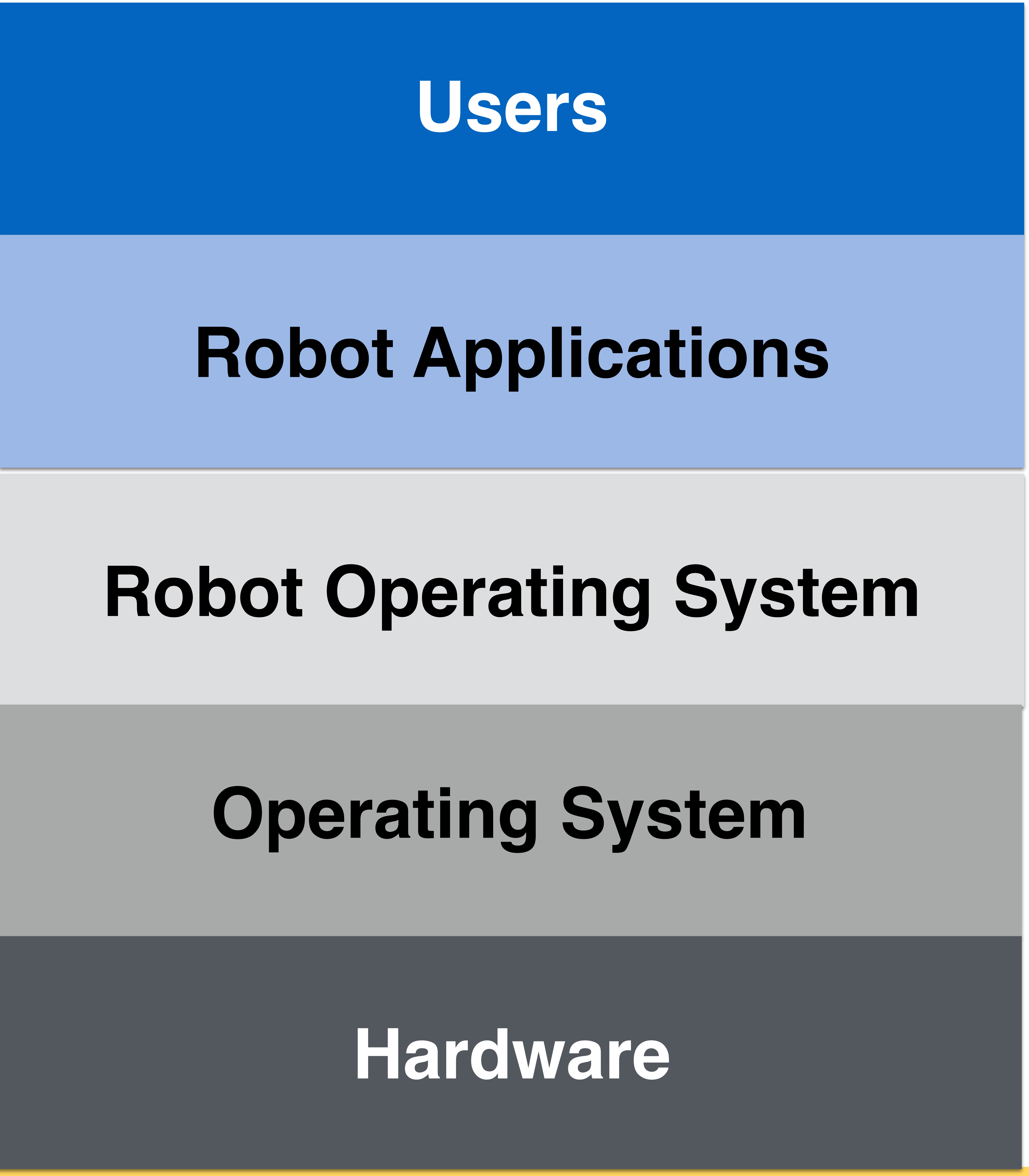

Users

Robot Applications

Robot Operating System

Operating System

Hardware

Work with a real robot once this semester

Turtlebot3

To be determined

Turtlebot4

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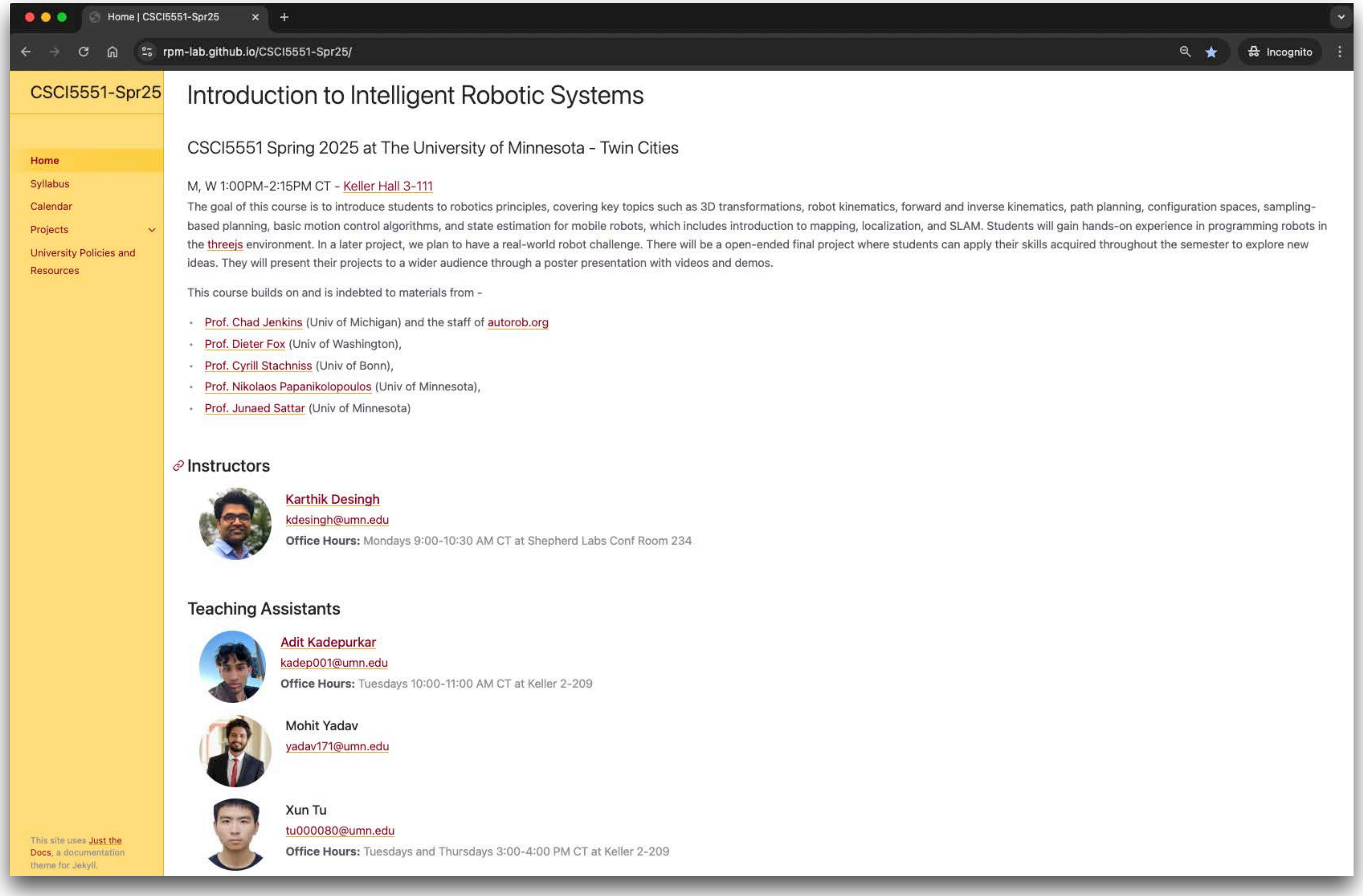
Course Resources

Course Website

https://rpm-lab.github.io/CSCI5551-Spr25/



Introduction to Intelligent Robotic Systems

CSCI5551 Spring 2025 at The University of Minnesota - Twin Cities

M, W 1:00PM-2:15PM CT - Keller Hall 3-111

The goal of this course is to introduce students to robotics principles, covering key topics such as 3D transformations, robot kinematics, forward and inverse kinematics, path planning, configuration spaces, sampling-based planning, basic motion control algorithms, and state estimation for mobile robots, which includes introduction to mapping, localization, and SLAM. Students will gain hands-on experience in programming robots in the threejs environment. In a later project, we plan to have a real-world robot challenge. There will be a open-ended final project where students can apply their skills acquired throughout the semester to explore new ideas. They will present their projects to a wider audience through a poster presentation with videos and demos.

This course builds on and is indebted to materials from -

- Prof. Chad Jenkins (Univ of Michigan) and the staff of autorob.org
- Prof. Dieter Fox (Univ of Washington),
- Prof. Cyrill Stachniss (Univ of Bonn),
- Prof. Nikolaos Papanikolopoulos (Univ of Minnesota),
- Prof. Junaed Sattar (Univ of Minnesota)

Instructors

Karthik Desingh
kdesingh@umn.edu
Office Hours: Mondays 9:00-10:30 AM CT at Shepherd Labs Conf Room 234

Teaching Assistants

Adit Kadepurkar
kadep001@umn.edu
Office Hours: Tuesdays 10:00-11:00 AM CT at Keller 2-209

Mohit Yadav
yadav171@umn.edu

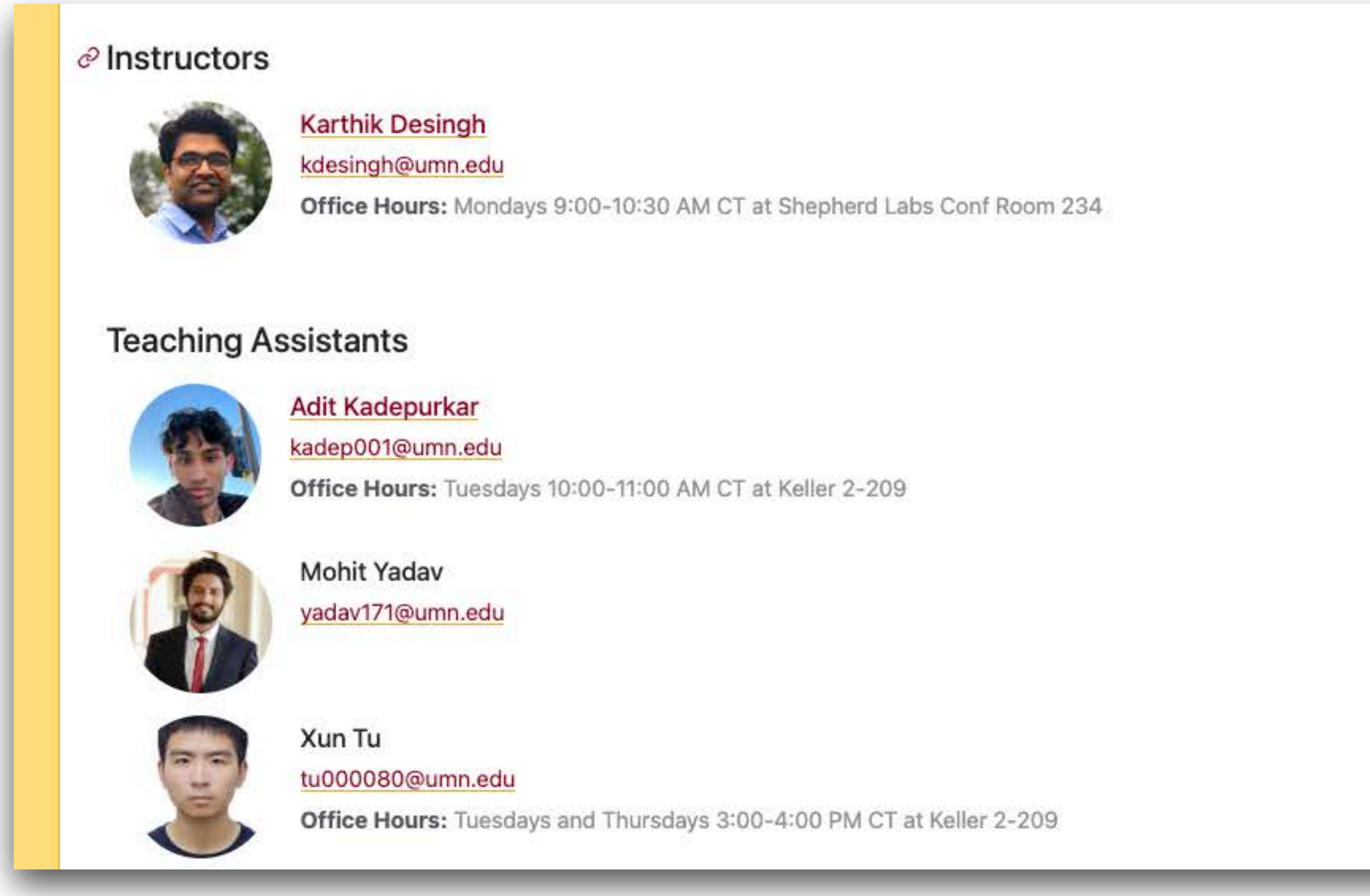
Xun Tu
tu000080@umn.edu
Office Hours: Tuesdays and Thursdays 3:00-4:00 PM CT at Keller 2-209

This site uses Just the Docs, a documentation theme for Jekyll.

Meeting Logistics

- **In-person Lectures**
  - Mon & Wed 1:00-2:15 PM CT
  - Keller Hall 3-111
  - UNITE recordings will be available with a 10 day delay

- **Office Hours**
  - Times posted on the website
  - Or by appointment



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kadep001@umn.edu
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Mohit Yadav
yadav171@umn.edu

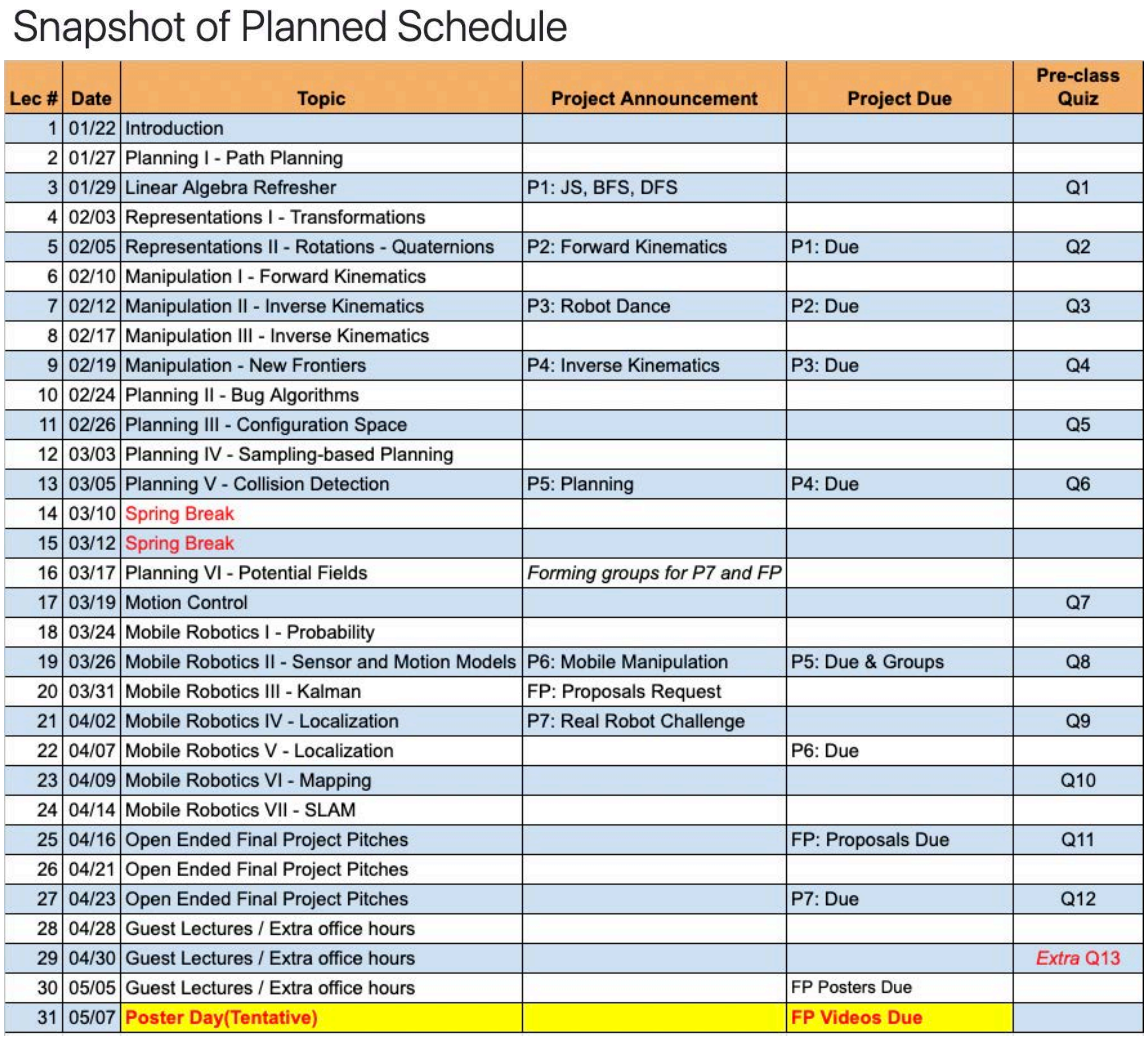
Xun Tu
tu000080@umn.edu
Office Hours: Tuesdays and Thursdays 3:00-4:00 PM CT at Keller 2-209

Course Structure

- **Objective:** Give you the computational skills to understand the nuts and bolts of developing a robotic system using kinematics and dynamics. Give you a broader idea of topics in robotics to further pursue advanced courses and research on these topics.
- **Project focused class:**
  - 7 total projects: building in complexity from basic transformations-rotations to motion planning and mobile manipulation

Course Schedule

https://rpm-lab.github.io/CSCI5551-Spr25/calendar/



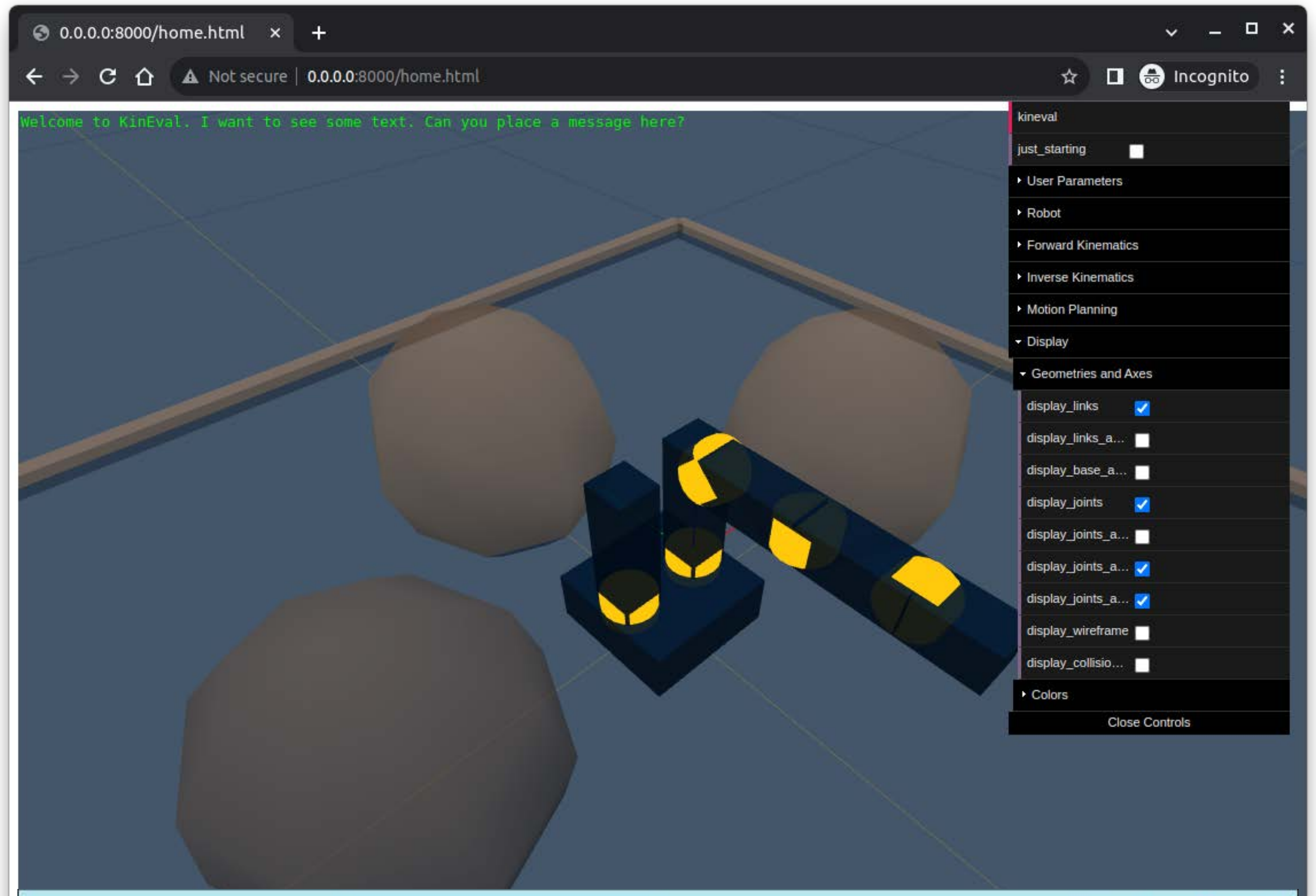
Snapshot of Planned Schedule

Lec #	Date	Topic	Project Announcement	Project Due	Pre-class Quiz
1	01/22	Introduction			
2	01/27	Planning I - Path Planning			
3	01/29	Linear Algebra Refresher	P1: JS, BFS, DFS		Q1
4	02/03	Representations I - Transformations			
5	02/05	Representations II - Rotations - Quaternions	P2: Forward Kinematics	P1: Due	Q2
6	02/10	Manipulation I - Forward Kinematics			
7	02/12	Manipulation II - Inverse Kinematics	P3: Robot Dance	P2: Due	Q3
8	02/17	Manipulation III - Inverse Kinematics			
9	02/19	Manipulation - New Frontiers	P4: Inverse Kinematics	P3: Due	Q4
10	02/24	Planning II - Bug Algorithms			
11	02/26	Planning III - Configuration Space			Q5
12	03/03	Planning IV - Sampling-based Planning			
13	03/05	Planning V - Collision Detection	P5: Planning	P4: Due	Q6
14	03/10	Spring Break			
15	03/12	Spring Break			
16	03/17	Planning VI - Potential Fields	*Forming groups for P7 and FP*		
17	03/19	Motion Control			Q7
18	03/24	Mobile Robotics I - Probability			
19	03/26	Mobile Robotics II - Sensor and Motion Models	P6: Mobile Manipulation	P5: Due & Groups	Q8
20	03/31	Mobile Robotics III - Kalman	FP: Proposals Request		
21	04/02	Mobile Robotics IV - Localization	P7: Real Robot Challenge		Q9
22	04/07	Mobile Robotics V - Localization		P6: Due	
23	04/09	Mobile Robotics VI - Mapping			Q10
24	04/14	Mobile Robotics VII - SLAM			
25	04/16	Open Ended Final Project Pitches		FP: Proposals Due	Q11
26	04/21	Open Ended Final Project Pitches			
27	04/23	Open Ended Final Project Pitches		P7: Due	Q12
28	04/28	Guest Lectures / Extra office hours			
29	04/30	Guest Lectures / Extra office hours			*Extra Q13*
30	05/05	Guest Lectures / Extra office hours		FP Posters Due	
31	05/07	**Poster Day(Tentative)**		**FP Videos Due**	

Guided Projects P1-P6 (Individual)

- Project 1
  - JS, BFS, DFS (Search and Planning)
- Project 2
  - Forward Kinematics
- Project 3
  - Robot dance

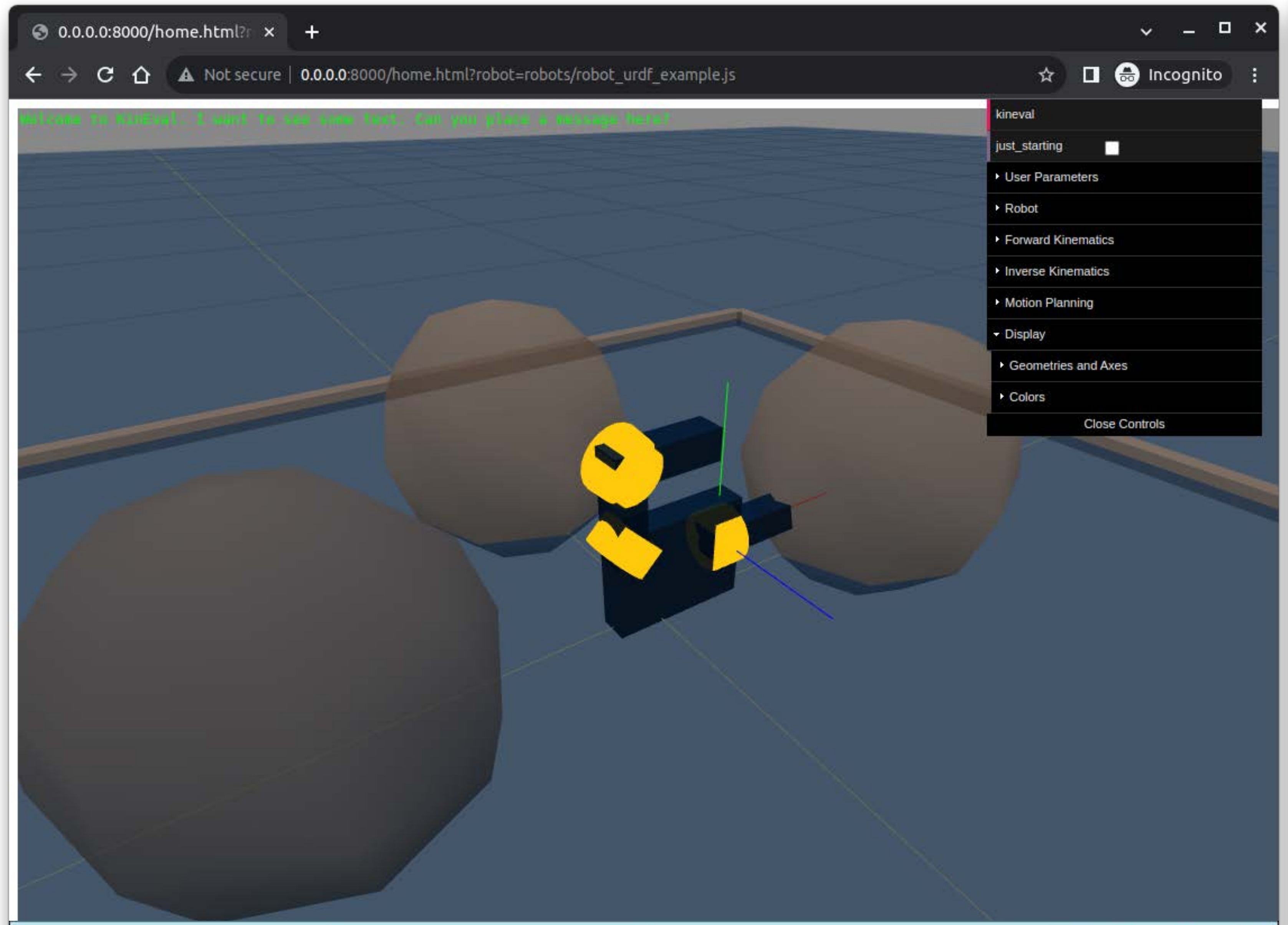
- Project 4
  - Inverse Kinematics
- Project 5
  - Planning
- Project 6
  - Mobile Manipulation



0.0.0.0:8000/home.html

Welcome to KinEval. I want to see some text. Can you place a message here?

kineval
just_starting ☐
User Parameters
Robot
Forward Kinematics
Inverse Kinematics
Motion Planning
Display
Geometries and Axes
display_links ☑
display_links_a... ☐
display_base_a... ☐
display_joints ☑
display_joints_a... ☐
display_joints_a... ☑
display_joints_a... ☑
display_wireframe ☐
display_collisio... ☐
Colors
Close Controls



0.0.0.0:8000/home.html?robot=robots/robot_urdf_example.js

Welcome to KinEval. I want to see some text. Can you place a message here?

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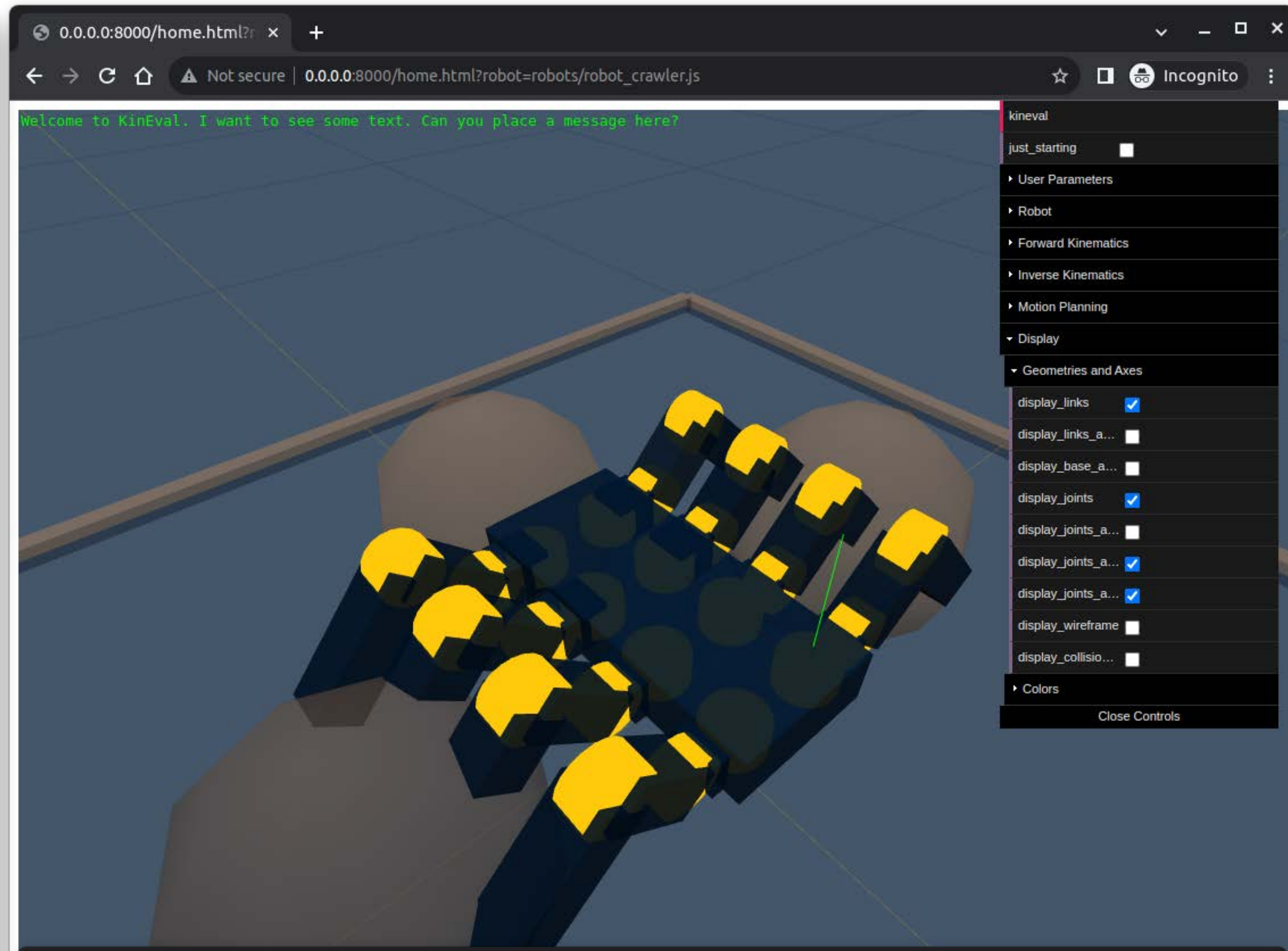
just_starting ☐
User Parameters
Robot
Forward Kinematics
Inverse Kinematics
Motion Planning
Display
Geometries and Axes
Colors
Close Controls



0.0.0.0:8000/home.html?robot=robots/robot_crawler.js

Welcome to KinEval. I want to see some text. Can you place a message here?

kineval
just_starting ☐
User Parameters
Robot
Forward Kinematics
Inverse Kinematics
Motion Planning
Display
Geometries and Axes
display_links ☑
display_links_a... ☐
display_base_a... ☐
display_joints ☑
display_joints_a... ☐
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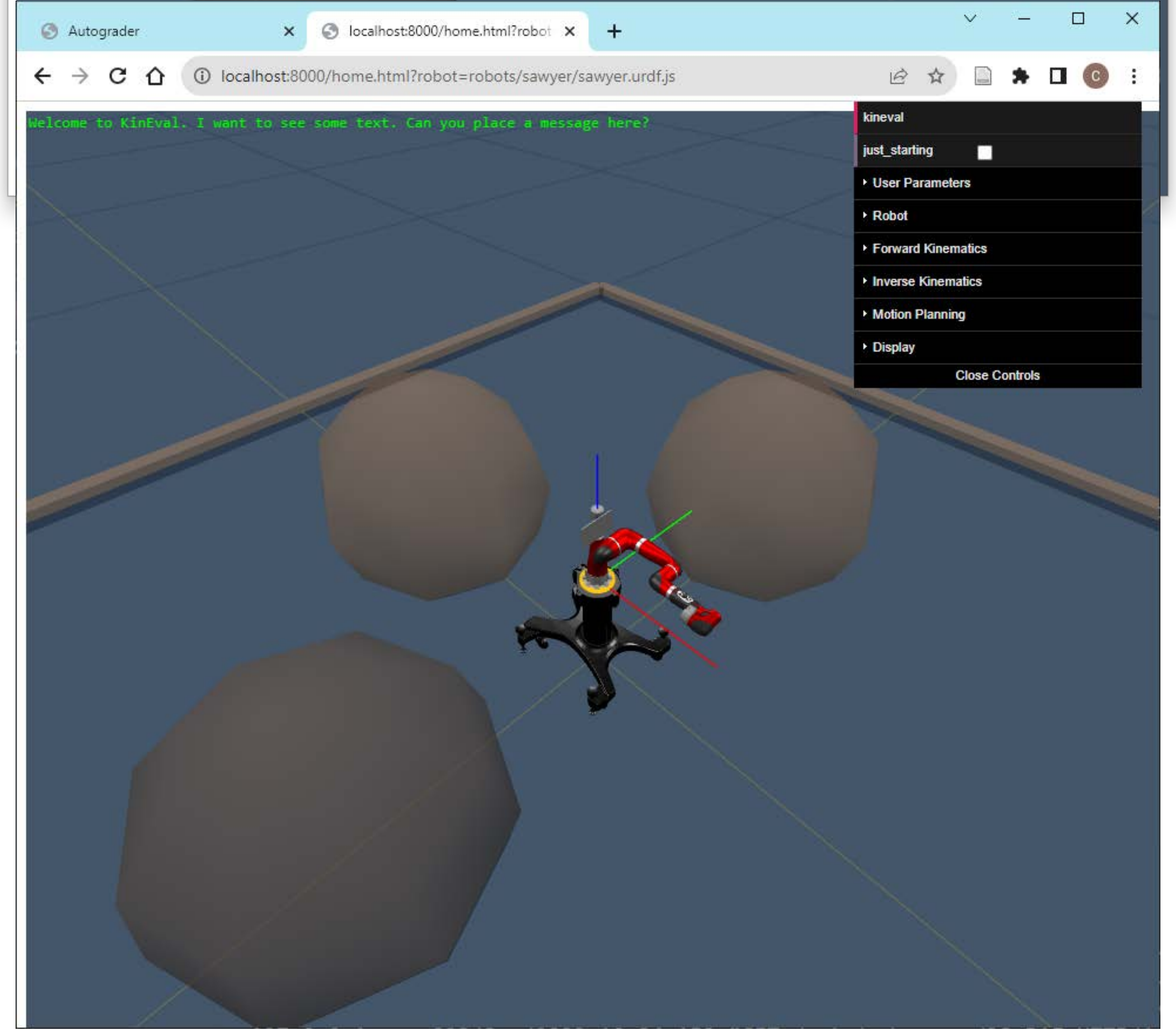
display_joints_a... ☑
display_wireframe ☐
display_collisio... ☐
Colors
Close Controls



localhost:8000/home.html?robot=robots/sawyer/sawyer.urdf.js

Welcome to KinEval. I want to see some text. Can you place a message here?

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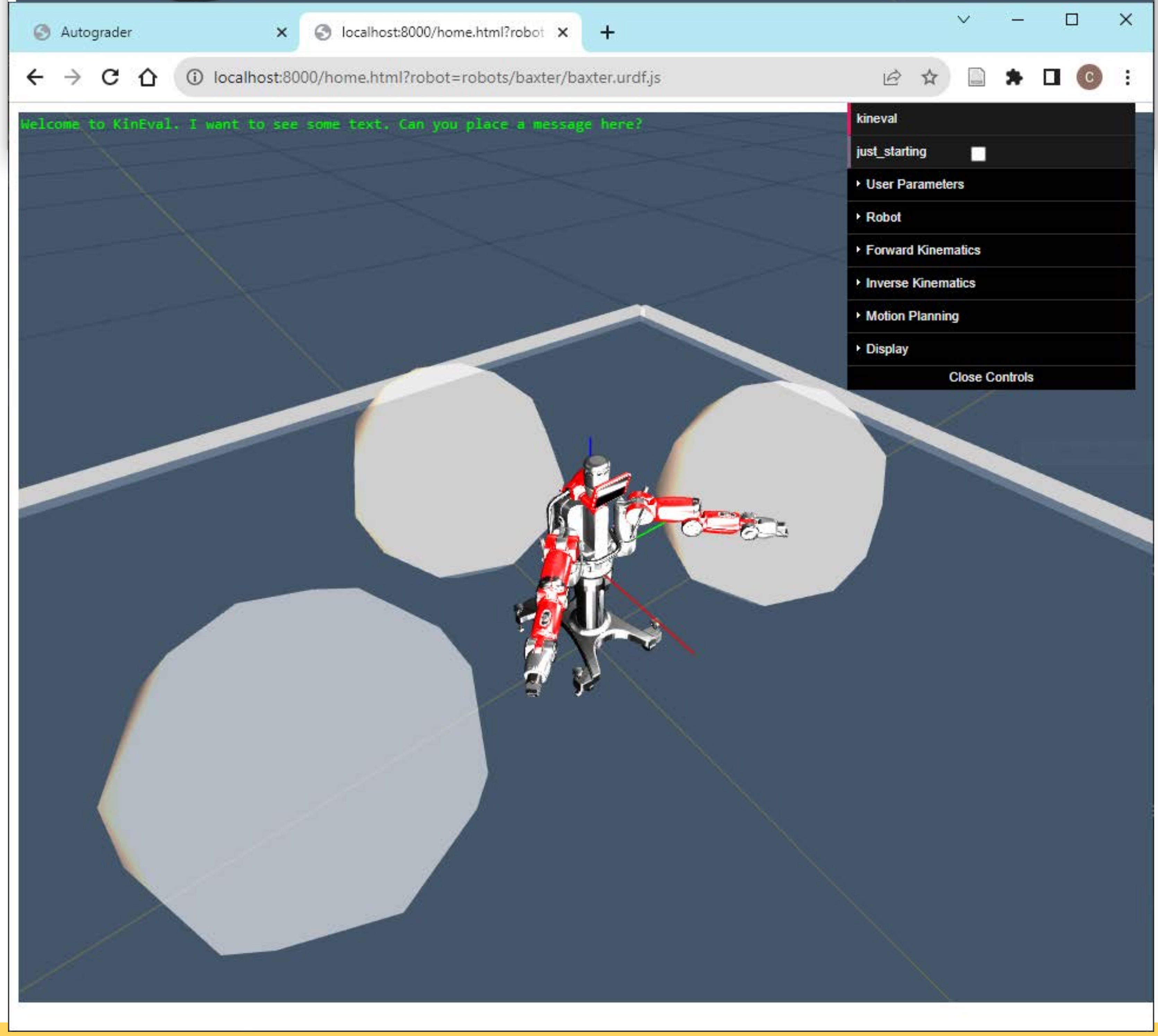
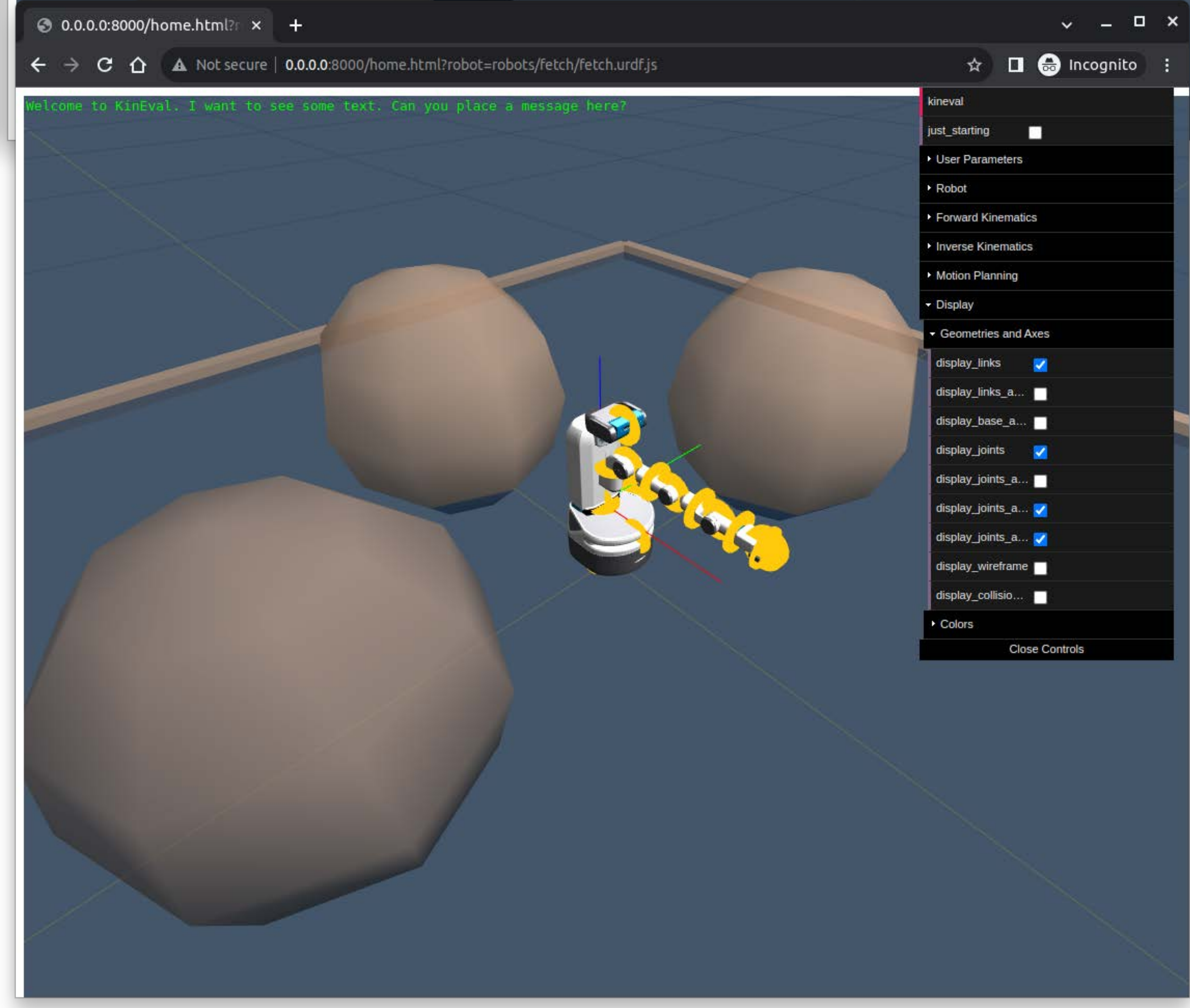
just_starting ☐
User Parameters
Robot
Forward Kinematics
Inverse Kinematics
Motion Planning
Display
Close Controls



localhost:8000/home.html?robot=robots/baxter/baxter.urdf.js

Welcome to KinEval. I want to see some text. Can you place a message here?

kineval
just_starting ☐
User Parameters
Robot
Forward Kinematics
Inverse Kinematics
Motion Planning
Display
Close Controls



0.0.0.0:8000/home.html?robot=robots/fetch/fetch.urdf.js

Welcome to KinEval. I want to see some text. Can you place a message here?

kineval
just_starting ☐
User Parameters
Robot
Forward Kinematics
Inverse Kinematics
Motion Planning
Display
Geometries and Axes
display_links ☑
display_links_a... ☐
display_base_a... ☐
display_joints ☑
display_joints_a... ☐
display_joints_a... ☑
display_joints_a... ☑
display_wireframe ☐
display_collisio... ☐
Colors
Close Controls

localhost:8000/home.htm
localhost:8000/home.html
kineval
just_starting ☑
User Parameters
Alt+A

Welcome to KinEval. I want to see some text. Can you place a message here?

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Not secure | 0.0.0.0:8000/home.html?world=worlds/world_mobile_manipulate.js
kineval
just_starting ☑
User Parameters
Robot
Forward Kinematics
Inverse Kinematics
Motion Planning
Mobile Manipulate
Display
Close Controls

Welcome to KinEval. I want to see some text. Can you place a message here?

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Not secure | 0.0.0.0:8000/home.html?robot=robots/fetch/fetch.urdf.js
kineval
just_starting ☑
User Parameters
Robot
Forward Kinematics
Inverse Kinematics
Motion Planning
Display
Close Controls

Welcome to KinEval. I want to see some text. Can you place a message here?

Guided Projects (Group)

- Project 7
  - Real Robot Challenge (**TBD**)

Turtlebot3

To be determined

Turtlebot4

Open-ended Final Project (Group)

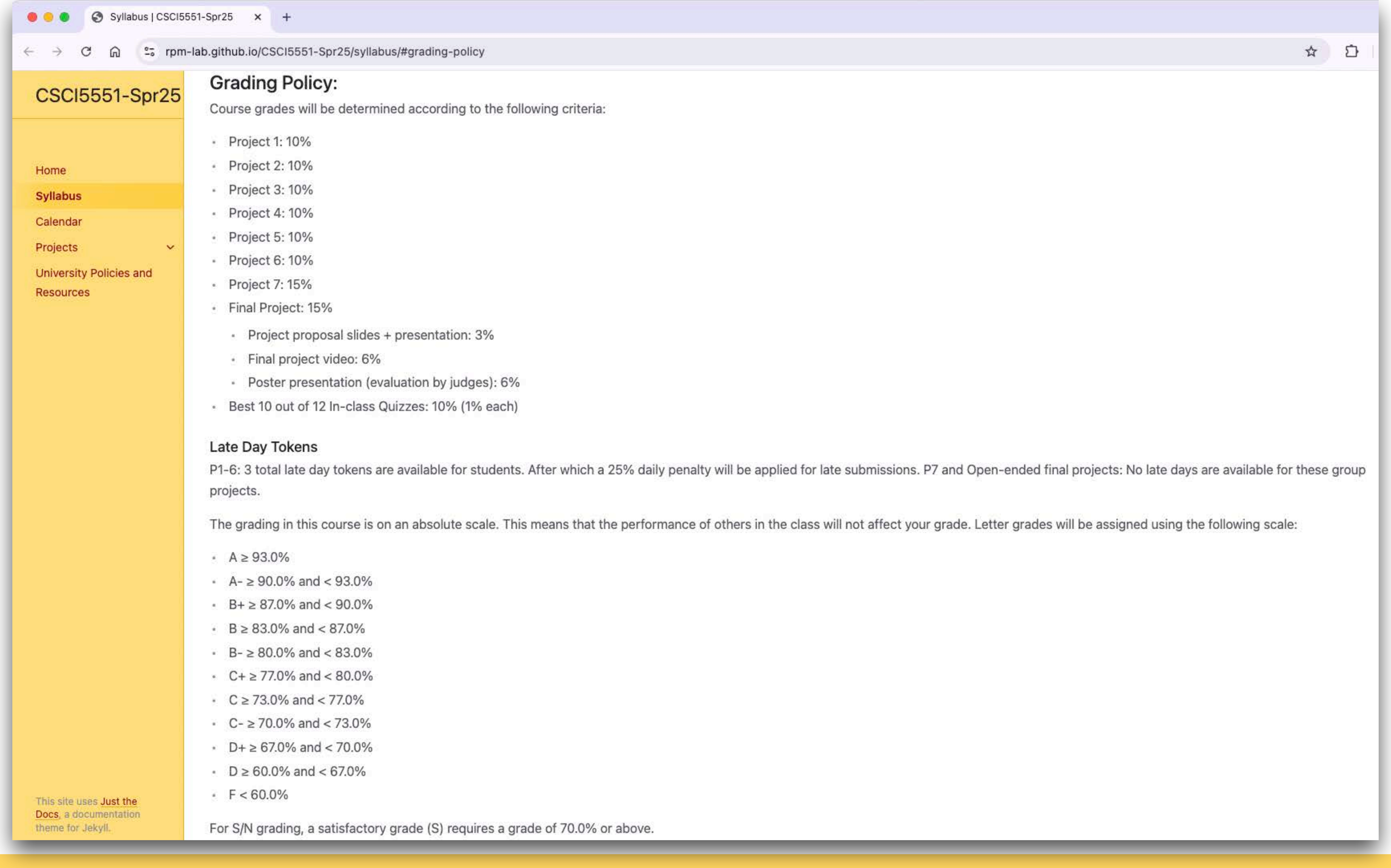
- Open-ended and will let student groups explore ideas with their learnings from the course.

Project Grading

- Guided Projects 1-6
  - 3 total late day tokens are available
  - 25% daily penalty after deadline, if you run out of late tokens.
- Guided Project 7
  - No late days
- Open-ended Final Project
  - No late days

Overall Grading Policy

https://rpm-lab.github.io/CSCI5551-Spr25/syllabus/#grading-policy


Syllabus | CSCI5551-Spr25
rpm-lab.github.io/CSCI5551-Spr25/syllabus/#grading-policy
CSCI5551-Spr25
Home
Syllabus
Calendar
Projects
University Policies and Resources
This site uses Just the Docs, a documentation theme for Jekyll.

Grading Policy:

Course grades will be determined according to the following criteria:

- Project 1: 10%
- Project 2: 10%
- Project 3: 10%
- Project 4: 10%
- Project 5: 10%
- Project 6: 10%
- Project 7: 15%
- Final Project: 15%
  - Project proposal slides + presentation: 3%
  - Final project video: 6%
  - Poster presentation (evaluation by judges): 6%
- Best 10 out of 12 In-class Quizzes: 10% (1% each)

Late Day Tokens

P1-6: 3 total late day tokens are available for students. After which a 25% daily penalty will be applied for late submissions. P7 and Open-ended final projects: No late days are available for these group projects.

The grading in this course is on an absolute scale. This means that the performance of others in the class will not affect your grade. Letter grades will be assigned using the following scale:

- A ≥ 93.0%
- A- ≥ 90.0% and < 93.0%
- B+ ≥ 87.0% and < 90.0%
- B ≥ 83.0% and < 87.0%
- B- ≥ 80.0% and < 83.0%
- C+ ≥ 77.0% and < 80.0%
- C ≥ 73.0% and < 77.0%
- C- ≥ 70.0% and < 73.0%
- D+ ≥ 67.0% and < 70.0%
- D ≥ 60.0% and < 67.0%
- F < 60.0%

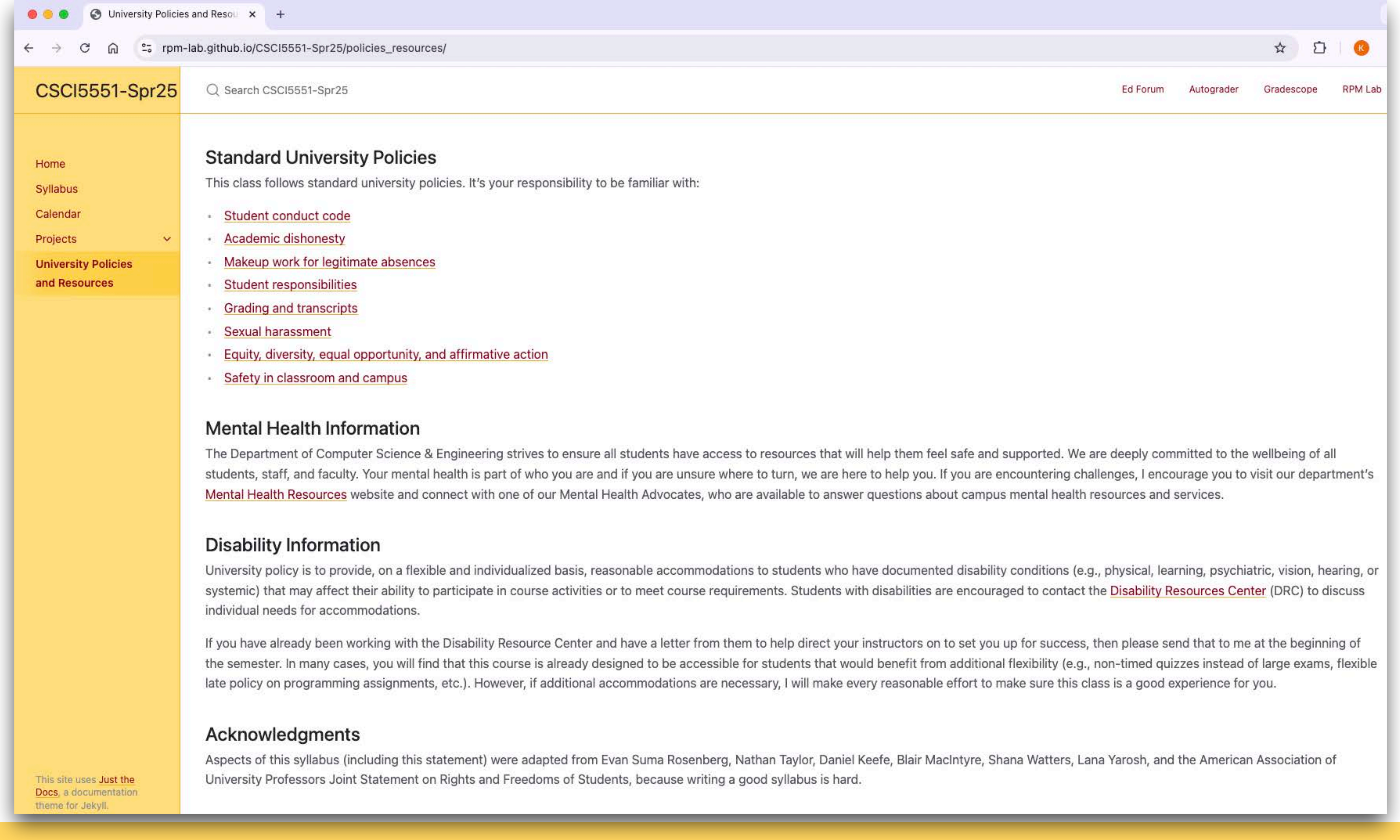
For S/N grading, a satisfactory grade (S) requires a grade of 70.0% or above.

Collaboration Policy

- All work submitted must be your own.
  - All code submitted must comply with College of Engineering Honor Code.
- Cheating will not be tolerated and can lead to termination from the program.
- No code can be communicated, including verbally.
  - Explicit use of external sources must be clearly cited.
- Free flow of discussion and ideas is encouraged.

University Policy

https://rpm-lab.github.io/CSCI5551-Spr25/policies_resources/



University Policies and Resou
rpm-lab.github.io/CSCI5551-Spr25/policies_resources/
CSCI5551-Spr25
Search CSCI5551-Spr25
Ed Forum
Autograder
Gradescope
RPM Lab
Home
Syllabus
Calendar
Projects
University Policies and Resources
This site uses Just the Docs, a documentation theme for Jekyll.

Standard University Policies

This class follows standard university policies. It's your responsibility to be familiar with:

- Student conduct code
- Academic dishonesty
- Makeup work for legitimate absences
- Student responsibilities
- Grading and transcripts
- Sexual harassment
- Equity, diversity, equal opportunity, and affirmative action
- Safety in classroom and campus

Mental Health Information

The Department of Computer Science & Engineering strives to ensure all students have access to resources that will help them feel safe and supported. We are deeply committed to the wellbeing of all students, staff, and faculty. Your mental health is part of who you are and if you are unsure where to turn, we are here to help you. If you are encountering challenges, I encourage you to visit our department's Mental Health Resources website and connect with one of our Mental Health Advocates, who are available to answer questions about campus mental health resources and services.

Disability Information

University policy is to provide, on a flexible and individualized basis, reasonable accommodations to students who have documented disability conditions (e.g., physical, learning, psychiatric, vision, hearing, or systemic) that may affect their ability to participate in course activities or to meet course requirements. Students with disabilities are encouraged to contact the Disability Resources Center (DRC) to discuss individual needs for accommodations.

If you have already been working with the Disability Resource Center and have a letter from them to help direct your instructors on to set you up for success, then please send that to me at the beginning of the semester. In many cases, you will find that this course is already designed to be accessible for students that would benefit from additional flexibility (e.g., non-timed quizzes instead of large exams, flexible late policy on programming assignments, etc.). However, if additional accommodations are necessary, I will make every reasonable effort to make sure this class is a good experience for you.

Acknowledgments

Aspects of this syllabus (including this statement) were adapted from Evan Suma Rosenberg, Nathan Taylor, Daniel Keefe, Blair MacIntyre, Shana Watters, Lana Yarosh, and the American Association of University Professors Joint Statement on Rights and Freedoms of Students, because writing a good syllabus is hard.

Discussion Forum

- EdStem is the discussion forum used in this course.
- Discussion of quizzes and verbatim code must be private.
- You will be added to it this week.

Next lecture:
Search Algorithms - Path Planning

Spot Robot Demo