European Master on Advanced Robotics Plus

Erasmus + programme
Agreement number 2014-2616/001-001
Coordinated by Ecole Centrale de Nantes

Erasmus Mundus Joint Master Degree EMARO+
"European Master on Advanced Robotics Plus"

STUDENT HANDBOOK

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1. Welcome

Welcome to the Erasmus Mundus Masters EMARO+. The purpose of this handbook is to explain **how EMARO+ works, and what you can expect from it**. The information is intended to help you find your feet and settle into postgraduate life as quickly as possible. The handbook outlines what you can **expect at each stage of** your **studies**, the **resources available**, the **structure and staffing within the members institutions**, and **procedures** for dealing with any problems you may encounter. Please read this handbook carefully as it is in your interest to familiarise yourself with the regulations and procedures. Students who are uncertain about the information in this handbook should ask their course coordinator. We hope you will find your time as a member of the postgraduate community rewarding and enjoyable.

2. Disclaimer

The Consortium has made all reasonable efforts to ensure that the information contained within this publication is accurate and up-to-date when published but can accept no responsibility for any errors or omissions. The Consortium reserves the right to revise, alter or discontinue modules and to amend regulations and procedures at any time, but every effort will be made to notify interested parties. It should be noted that **not every module listed in this handbook may be available every year, and changes may be made to the details of the modules**.

3. EMARO+ at a Glance

EMARO+ is an integrated Masters course conducted by **four European institutions**: Ecole Centrale de Nantes -ECN- (France), Warsaw University of Technology –WUT- (Poland), the University of Genoa –UG- (Italy), Jaume I University –UJI- (Spain) and involves **7 associated partners**: Faculty of Science an Technology of KEIO University (Japan) and Shanghai Jiao Tong University (China), IRT Jules Verne (France), Airbus Group Innovations (France), BA Systemes (France), Robotnik (Spain), SIIT (Italy).

Objectives:

The Master EMARO+ is designed in the framework of ERASMUS MUNDUS programme to **promote a high-quality educational offer in the area of advanced and intelligent robotics**. After graduation, the students will have mastered the different areas of robotics (Mathematical modeling, Control Engineering, Computer Engineering, Mechanical design) in order to be able to deal with Robotics systems as a whole rather than just to concentrate on one particular area. The career prospects for EMARO+ graduates are very good as the proposed courses are relevant to today's high technology society and because the current output of universities is insufficient to meet the demands of industry and research programmes. Students may take the master as a professional terminal degree, or join PhD programmes afterwards.

Duration and mobility:

The programme of study lasts **two academic years (120 ECTS)**, split into four equally loaded semesters. The student has to spend the **first two semesters in one European institution** and the **second two semesters in another European institution**. An **optional mobility** can be done (after the acceptance of the programme committee) during the **fourth semester** and to complete the Master thesis, to any Industrial partner or other institution of the Consortium (ECN, WUT, UG, UJI, KEIO, SJTU). This mobility will not modify the degrees awarded; the student will obtain the master degrees of the institutions of first and third semesters only.

Notes:

- Erasmus Mundus scholarship holders must carry out their mobility inside the consortium only (at partner or associate partner institutions),
- The Management Committee shall approve each mobility.

Summary of study programme:

The **language of instruction and examination** is **English**, but **local language and culture courses** of the hosting countries are **included in** the **programme** of study. The aim of the first two semesters is to provide the students with a solid interdisciplinary background across the main areas of robotics (Cognition, Action, Perception). During the third semester, depending on the host institution, the student will deal with one or more of the following sectors: industrial robot systems, service robots (domestic, health, rehabilitation, leisure), biorobotics, humanoidand security robots. The fourth semester is dedicated to the Masters Thesis. The student carries out his/her research work under the joint supervision of at leat two advisors from two (or three) different consortium institutions.

Degrees awarded:

Students that graduate from the EMARO+ masters course will **obtain two masters degrees** from the institutions where they studied the first and third semesters. The obtained degrees are officially recognised and give full access to PhD study programmes.
The Consortium will deliver Diploma supplement describing the nature, level, context, content and status of the studies that were pursued and successfully completed by the student.

Admission Requirements:

The Masters course applies to European and third country-students who already hold a first university degree with **180 ECTS**, **after at least three years of university studies** (at the level of bachelor of science), in a field related to Robotics, such as: automatic control, mechatronics, computer science, electrical engineering, mechanical engineering, and applied mathematics. The applicants have to be fluent in writing and reading in English (TOEFL (score 220 CBT, 550 PBT, 80 IBT), Cambridge Advanced English Test (score B or higher), IELTS (score 6.5 or higher), TOEIC (800). The admission is decided on the basis of excellence of the academic records of the student, the quality of her/his former studies, motivations, reference letters and general skills for foreign languages.

4. Calendar

Each institution will provide to students a precise calendar key dates with dates of exams, holidays.

The first and third semester start on 1st September and finish on 31st January. The second and fourth semester start on 1st February and finish on 31st August.

5. Important links and Resources:

Emaro+ students have an access to the following resources of the host institution:

- Library,
- Rooms equipped with computers
- WiFi.
- List and contact of teachers/researchers involved in the programme

Details and operating procedure will be precise by the host institution at the beginning of the academic year.

6. Structure of the programme of M1

The structure of the first year, M1, is shown in Table 1. It consists of two semesters S1 (from September till the beginning of February) and S2 (from February till the end of June). The first semester starts with eight days of intensive local language course. The objectives, contents, assessments, etc. of all the modules are given in Annex 1.

Table 1: Structure of the first year

First eight days (September)	First semester (30 ECTS)	Second semester (30 ECTS)
- Local language course	- Interdisciplinary background - Local language course	- Interdisciplinary background Modules - Local language course*

* with 3 ECTS to be metionned in the Diploma Supplement in case of success.

6.1. The first semester modules (details in Annex 1)

The student will select six modules (30 ECTS) from the following:

Modules	**Lecturers**	**ECTS**
Local language (compulsory)	Language departments in ECN, WUT or UNIGE	4
Modelling and control of manipulators (compulsory)	P. MARTINET (ECN), C. ZIELINSKI (WUT), CASALINO (UNIGE), A. MORALES (UJI)	6
Control of linear multivariable systems	G. LEBRET (ECN), G. CANNATA (UNIGE), J. M. SANCHIZ (UJI)	5
Basics of Automation and Control 1	C.Rzymkowski (WUT)	5
Real-time systems	T. KRUK (WUT), M.CHETTO (ECN), F. PLA (UJI), A. Sgorbissa (UNIGE)	5
Signal processing	W. KASPRZAK (WUT), E. LE CARPENTIER (ECN), P. GARCÍA (UJI)	5
Advanced and Robot Programming	F. MASTROGIOVANNI (UNIGE), G. GARCIA (ECN), R. ZACCARIA (UNIGE)	5
Computer science	J. ROKICKI	5
Computer vision	W. KASPRZAK (WUT), P. MARTINET (ECN), F. Solari/S. SABATINI (UNIGE), F. PLA (UJI)	5
Neural networks for classification and identification	G. ORZECHOWSKI (WUT)	5
Visiting course	**To be given by a scholar from the Partner-country partners**	**5**

6.2. The second semester modules (details in Annex 1)

The student will select seven modules (30 ECTS) from the following:

Modules	**Lecturers**	**ECTS**
Group Project (compulsory)	Various local staff	5
Mechanical design methods in robotics	K. MIANOWSKI (WUT), S. CARO (ECN), D. Chablat (ECN), D. Zlatanov, M. Zoppi (UNIGE), C. Vila (UJI)	5
Software architectures for robotics	F. MASTROGIOVANNI (UG) and G. GARCIA (ECN)	5
Robot Programming Methods	C. ZIELINSKI (WUT)	5
Mobile robots	P. MARTINET (ECN), G. GARCIA (ECN), R. ZACCARIA (UNIGE), W. SZYNKIEWICZ (WUT), J. SALES (UJI)	5
Artificial intelligence	W. KASPRZAK (WUT), C. ZIELINSKI (WUT), A. TACCHELLA (UNIGE), E. MARTINEZ (UJI), R. ZACCARIA (UNIGE)	5

Optimisation techniques	F. BENNIS (ECN), W. OGRYCZAK (WUT), C. NATTERO (UNIGE)	5
Nonlinear control	F. PLESTAN, C. MOOG (ECN)	5
Embedded systems	S. DENEI (UNIGE)	5
Visiting course	**To be given by a scholar from the Partner-country partners**	**5**

7. Structure of the programme of M2

7.1 The third semester modules (details in Annex 1)

The student will select six modules from the following (30 ECTS):

Modules	**Lecturers**	**ECTS**
Local language (compulsory)	Language departments in ECN, WUT, UJI or UNIGE	4
Research methodology (compulsory)	I. Taralova (ECN), R. Berlanga (UJI), G. Quintana (UJI), T. Zielinska, C. Zielinski (WUT)	6
Sensor based control of complex robots	P. Martinet (ECN), O. Kermorgant (ECN)	4
Advanced modelling of Robots	S. Briot (CNRS), S. Caro (CNRS)	4
Humanoid robots	C. Chevallereau (CNRS), Y. Aoustin (Univ. Nantes)	4
Optimal kinematic design of robots	P. Wenger (CNRS)	4
Autonomous vehicles	P. Martinet (ECN), E. Le Carpentier (ECN), C. Laugier (Inria)	4
From human motion to humanoid control	S. Sakka (ECN)	4
Advanced Visual Geometry	O. Kermorgant (ECN), D. Marquez Gamez (IRT)	4
Robotic Intelligence	AP. Del Pobil (UJI)	5
Perception and manipulation	PJ. Sanz (UJI)	5
Cooperative robotics	E. Cervera (UJI)	5
Ambient intelligence	JV. Marti (UJI)	5
Telerobotics	R. Marin (UJI)	5
Biomechanics (compulsory)	K. Kedzior, C. Rzymkowski (WUT)	5
Bio-robotics (compulsory)	T. Zielinska (WUT)	5
Dynamics of multi-body systems	J. Frączek, M. Wojtyra (WUT)	5
Advanced mechanical design	K. Mianowski (WUT)	5
Visiting course	To be given by a scholar from the Partner-country partners	5

7.2 The fourth semester

The fourth semester is devoted to the Master Thesis, valued for 30 ECTS credits.

Annex 1. Syllabus of the first year modules

A1.1 The first semester modules

French, Italian, Polish, Spanish Language		
Credits: 4 Semester 1 **Compulsory: Yes**		
Format	Lectures / Conversation 50 h	Private study 50 h
Lecturers: Language departments in ECN, WUT, UJI and UNIGE		
Objectives: Allow the student to achieve a sufficient oral and written comprehension of the local language of the hosting country. As well as an introduction to country culture. **Organization:** The language will be offered in 2 options: Beginners; Advanced (for those who have a previous experience in the language); **Contents:** Culture lectures, conversations, reading, and writing exercises		
Abilities: After completing this course: The students will be able to communicate, speak and write, everyday life requirements, The advanced group will be able also to read and write texts related to scientific topics.		
Assessment: 50% of the mark derived from a continuous evaluation, 50% derived from a final exam.		
Recommended texts: the texts will be given by tutors		

Modelling and control of manipulators

Credits: 6 Semester 1
Compulsory: Yes

Format	Lectures 30 h	Examples 20 h	Private study 100 h

Lecturers: P. MARTINET (ECN), C. ZIELINSKI (WUT), G. CASALINO (UNIGE), A. MORALES (UJI)

Objectives: This course presents the fundamentals of the modelling and control techniques of serial manipulators. Topics include robot architectures, geometric modelling, kinematic modelling, dynamic modelling and its applications, classical PID controller and computed torque controller.

Contents:
The following subjects will be treated:

- Robot architectures, joint space, operational space;
- Homogenous transformation matrices;
- Description of manipulator kinematics using modified Denavit and Hartenberg notations;
- Direct geometric model;
- Inverse geometric models using Paul's method, Piper's method and general methods;
- Calculation of kinematic Jacobian matrix;
- Inverse kinematics for regular and redundant robots;
- Dynamic modelling using Lagrange formalism;
- Dynamic modelling using recursive Newton-Euler method;
- Trajectory generation between two points in the joint and operational spaces,
- Classical PID control
- Computed torque Control.

Practical Work: Exercises will be set, which will involve modelling some manipulators, and simulation of control laws.

Abilities: After completing this course the students will be able to:

- Understand the fundamentals of the mathematical models of serial robot manipulators and their applications in robots design, control and simulation.
- Understand the effect of the kinematic parameters on the manipulator characteristics.
- Use the most convenient methods to obtain the required models,
- Understand practical applications of the mathematical modelling of manipulators,
- Use symbolic and numerical software packages (Matlab, Simulink, Maple, Mathematica, …).
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Assessment: 30% continuous assessment, 70% from end of semester examination.

Recommended texts:

- W. Khalil, and E. Dombre, *Modelling, identification and control of robots*, Hermes Penton, London, 2002.

Further readings:

- C.Canudas, B. Siciliano, G.Bastin (editors), *Theory of Robot Control*, Springer-Verlag, 1996.
- J. Angeles, *Fundamentals of Robotic Mechanical Systems,* Springer-Verlag, New York, 2002.

Control of linear multivariable systems			
Credits: 5 Semester 1 **Compulsory: No**			
Format	Lectures 25 h	Examples 15	Private study 85 h
Lecturer: G. LEBRET (ECN), G. CANNATA (UNIGE), J. M. SANCHEZ (UJI)			

Objectives: The aim of the course is to give a methodology for the design of a control law for multivariable linear time invariant systems (MIMO LTI systems). This methodology is developed in the state space approach and is based on the concept of the "Standard Problem".

Contents:
The following subjects will be addressed:

State space equations and solutions.
Controllability, observability.
Static state feedback control law.
Observer synthesis and observer based controller.
Specification of a control problem in terms of a standard problem.
Regulator problem with internal stability,
Internal model principle,
Linear quadratic method of regulator synthesis,
The concept of robustness by loop transfer recovery,
Optimization H2 (or LQG),
Methodology of control of multi-variable systems.

Practical Work: Control of different laboratory systems using Matlab and dspace.

Abilities: After completing this course the students will be able to:

1. analyze the properties (controllability, …) of a linear multivariable systems,
2. design an observer based controller,
3. define the standard problem (multivariable servo-regulation problem) for a linear (or linearized) multivariable system,
4. give a solution to the standard problem which insure robust stability and robust asymptotic performances to the closed loop system.

Assessment: 30% continuous assessment, 70% from end of semester examination.

Recommended texts: The notes of the course will be given by lecturer..

Further readings:

- T. Kailath, *Linear Systems*. Prentice-Hall, New Jersey, 1980.
- G.F. Franklin, J.D. Powell and A. Emami-Naeini, *Feedback Control of Dynamic Systems* (Second Edition). Addison-Wesley, 1991.
- K.J. Aström, B. Wittenmark, *Computer-Controlled Systems, Theory and Design*. Prentice Hall, New Jersey, 1990.
- W.M.Wonham, *Linear Multivariable Control: A Geometric Approach* (Third Edition). Springer Verlag, New York, 1985.
- K. Zhou, with J. Doyle Essentials of Robust Control (Third Edition). Prentice Hall, New Jersey,1998.

Real-time systems

Credits: 5 Semester 1
Compulsory: No

Format	Lectures 25 h	Guided project 15 h	Private study 85 h

Lecturer: B.J. KUBICA (WUT), M. CHETTO (ECN), F. Pla (UJI), A. SGORBISSA (UNIGE)

Objectives: By attending the course, the student will learn how to deal with issues concerning real-time applications and real-time operative systems, real-time design and programming, embedded systems.

Contents:

Real-time operating systems

- Basic principles;
- Real-time scheduling algorithms for periodic tasks: Rate Monotonic, arliest
- Deadline First, Deadline Monotonic;
- Real-time scheduling algorithms for aperiodic tasks: scheduling in background,
- Polling Server, Deferrable Server;
- Protocols for accessing shared resources: Priority Inheritance, Priority Ceiling.

Soft real-time systems

- Real-time programming in Posix;
- Thread, mutex and conditional variables;
- Rate Monotonic on Posix Linux;
- Periodic servers;
- Interprocess communication for real-time systems.

Hard real-time systems

- QnX, VxWorks, Windows CE
- RTAI: periodic and aperiodic tasks; communication mechanisms.

Fundamentals of real-time programming for embedded systems.

- General overview of existing families of micro-controllers, DSPs, FPGAs, ASICs.
- Basics of development for embedded systems: coding, compiling, linking, downloading, executing.
- Different kinds of memory devices and memory organization; basic I/O operations; Buses and communication channels.
- Interrupt-driven programming.

Abilities: At the end of the course the student will be able to

- Correctly state and solve problems concerning the design of real-time applications,
- Implement real-time applications in Linux Posix and RTAI;
  - Design event-driven, embedded real-time applications for micro-controllers.

Assessment: 30% laboratory work, 70% end of semester examination.

Recommended texts:

- Giorgio C. Buttazzo, Hard Real-time Computing Systems, Kluwer Academic publishers, 1997.
- Q. Li, C. Yao. Real-Time Concepts for Embedded Systems. CMP Books, 2003.

Further readings:

- will be provided by lecturer.

Basics of Automation and Control			
Credits: 4 Semester 1 **Compulsory: No**			
Format	Lectures 30 h	Examples 15	Private study 85 h
Lecturer: C.Rzymkowski (WUT)			

Objectives: The aim of the course is to give a methodology for the design of a control law for multivariable linear time invariant systems (MIMO LTI systems). This methodology is developed in the state space approach and is based on the concept of the "Standard Problem". Introduction to mathematical modelling - Laplace Transform as analysis and design tool for Control Systems. Transient and Frequency response analyses. Stability system analyses.

Contents:
The following subjects will be addressed:
The objective of the course is to gain the following abilities:
- ability to transform the functions using Laplace transform,
- ability to describe the control system in Laplace domain,
- ability to create and simplify the block diagrams of controled objects,
- ability to evaluate the typical system responses for standard inputs,
- ability to describe and analyse the control system in time and frequency domains.
- applying basic stability criteria.

Practical Work: Control synthesis of basic systems

Signal processing

Credits: 5 Semester 1
Compulsory: No

Format	Lectures 25h	Tutorials 15h	Private study 85 h

Lecturers: W.Kasprzak (WUT), E.Le Carpentier (ECN), P. García (UJI)

Objectives: To present the methods of description and transformation of deterministic signals for both continuous and discrete time cases. To present also basic knowledge about random signals representation.

Contents:

Analog and digital signal conversion.
Continuous and discrete signal processing.
Linear and nonlinear systems.
Common signal decompositions.
Convolution – its principle and impulse response.
Common impulse responses, convolution properties, correlation.
Fourier transform properties: applications of Fourier transform - spectral analysis of signals, frequency response of systems.
Discrete Fourier transform. Fast Fourier transform.
Introduction to digital filters. Moving average filters. Windowed-sinc filters. De-convolution and optimal filters. Recursive filters. The z-transform and Chebyshev filters. Audio and image processing.
Random signals: summary on random variables: cumulative distribution, probability density function, joint and marginal distributions;
Random signal characterization; basic properties: stationarity, ergodicity, broad-sense stationarity;
Basic signals: definition and validity domain;
Time analysis (correlation) and spectral analysis (power spectral density) of stationary signals;
Fourier analysis, Wiener-Khintchine theorem;

Abilities: The students will be able to:

Represent continuous signals by their discrete equivalents,
Decompose complex signals,
Analyze the signals in Fourier domain,
Design the basic filters for signals processing,
Apply the filter to process the signal,
Analyze random signals

Assessment: 30% continuous assessment, 70% from end of semester examination.

Recommended texts:

[1] Steven W. Smith, *The Scientist and Engineer's Guide to Digital Signal Processing*. Second Edition, California Technical Publishing, San Diego, CA, 1999, on-line: www.dspguide.com.

[2] A.V. Oppenheim, R.W. Schafer, J.R. Buc, *Discrete-Time Signal Processing. Second Edition.* Prentice-Hall 1999.

Further readings: will be provided by lecturer.

Computer Science 1			
Credits: 5 Semester 1 **Compulsory: No**			
Format	Lectures 30	Laborsatories: 30h	Private study 85 h
Lecturers: J.Rokicki (WUT)			

Objectives: To give the students the fundamentals of programming skills and methods.

Contents:
Basic information related to operating systems and computer networks. Word-processing and spreadsheets used in typical engineering applications. Programming language C - variables and their types, arithmetical and logical operations, control statements, functions, tables and pointers, structures.
Input and Output. Code examples. Basic algorithms (sorting), simple numerical methods. Practical programming skills.

Advanced and Robot Programming			
Credits: 5 Semester 1 **Compulsory: No**			
Format	Lectures 16 h	Tutorials/Labs 32 h	Private study 50 h
Lecturers: F. MASTROGIOVANNI (UNIGE), G. GARCIA (ECN), R. ZACCARIA (UNIGE)			

Objectives: To give the students the fundamentals of:
- C++ programming
- Industrial robot manipulator programming using specialized robot languages.

Contents:
- C++ programming
  - Functions, passing by value and by reference, constant references, pointers.
  - Static and dynamic arrays, multi-dimensional arrays, vectors, strings.
  - Classes, objects, attributes, methods, heritage, virtual methods.
  - Code organization.
  - Operator overloading.
  - Using C++ libraries.
- Industrial manipulator programming
  - The different levels of programming,
  - Tools for teaching locations,
  - Robots, sensors and flexibility,
  - Synchronous vs asynchronous motions, guarded motions,
  - Tool-level programming,
  - Object level programming,
  - Real-time aspects of robot programming,
  - The V+ language, including its real-time aspects and sensor-handling capabilities.
  - Introductory concepts about ROS

Practical Work: C++ labs are essentially oriented towards understanding and using C++ libraries and good programming practice.
As to industrial robot programming, the students will be able to practice with a setup of two

Stäubli industrial robots, a Puma 560 and a RX 90 programmable in V+. The robots are equipped with a belt conveyor, and a number of sensors.
Abilities: After completing this course, the students will be able to: • Program in C++, especially using existing libraries like openCV. • Analyze, program and test complex tasks on industrial robots in V+.
Assessment: 50% continuous assessment, 50% from end of semester examination.
Recommended texts: 1. C. Blume, W. Jakob, *Programming Languages for Industrial Robots*, Springer Verlag. 2. Stäubli: RX Robots Technical Documentation, 2001. 3. Bruce Eckel, Thinking in C++, volumes 1 and 2, 2007. **Further readings:** will be provide by the lecturer

Computer vision

Credits: 5 Semester 1 **Compulsory: No**			
Format	Lectures 24h	Tutorials/examples 16h	Private study 85h
Lecturers: W.KASPRZAK (WUT), P. MARTINET (ECN), F. SOLARI/S. SABATINI (UNIGE), F. PLA (UJI)			

Objectives:
This course presents the fundamentals in computer vision. Topics include camera modelling, camera calibration, image processing, pose estimation, multi view geometry, visual tracking, and vision based calibration.

Contents:
Image formation and auto-calibration. Low-level image processing: image normalization, colour spaces, image compression and image filtering. Image segmentation: edge detection, chain and line segment detection, Hough transforms, homogeneous region-, shape- and texture description. Object classification: the potential functions-, Bayes-, k-NN, SVM- and MLP- classifiers. Object recognition: dynamic programming, hypothesis generation-and-test, model-to-image matching and graph search. Image motion estimation: gradient- and block-based optical flow, discrete feature motion and active contour tracking. Camera technology and vision sensor, Camera model (pinhole, omnidirectional, fisheye, …), Visual geometry, Pose estimation (DeMenthon, Lowe…), Multi view geometry (homography, epipolar geometry, …), Visual tracking, calibration (camera, robots…), Computer vision applications, Computer vision tools

Practical Work: Exercises will involve image processing, multi view geometry, camera calibration, pose estimation, visual tracking, Face recognition.

Abilities: The students will be able to:
Know the different image processing methods,
Understand the different properties of images, cameras and geometry
To select the image processing method for the specific purpose.
Process the images for the purpose of getting the required information.
To use the vision for objects recognition and robot localization and guidance
Understand practical applications of the mathematical modelling of visual geometry

Assessment: 30% continuous assessment, 70% from end-semester examination

Recommended texts:

- I. Pitas, *Digital Image Processing Algorithms*, Prentice Hall, New York, 1993.
- O. Faugeras, *Three-dimensional computer vision. A geometric viewpoint*, The MIT Press. Cambridge, Mass. 1993, ISBN: 0262061589
- Richard Hartley, Andrew Zisserman, *Multiple View Geometry in Computer Vision*, Barnes&Nobles, 2nd edition 2004, ISBN-10: 0521540518
- Quang-Tuan Luong, Olivier Faugeras, *The Geometry of Multiple Images- The Laws That Govern the Formation of Multiple Images of a Scene*, MIT Press, March 2001, ISBN: 0-262-06220-8
- T S Huang, *Multiple Calibration and Orientation of Cameras in Computer Vision*, Springer, 2001, ISBN: 3 540 65283 3
- Yi MA, Stefano Soatto, Jana Kosecka, S. Shankar Sastry, *An invitation to 3D vision: from images to geometric models*, Springer, 2004, ISBN 978-0-387-00893-6
- Gari Bradski, Adfrian Kaebler, *Learning OpenCV: Computer vision with openCV library*, O'Reilly Media, 2008, ISBN: 978-0-596-51613-0

Further readings: will be provided by lecturer

Neural networks for classsification and identification

Credits: 5 Semester 1
Compulsory: No

Format	Lectures 30h	Tutorials 15h	Private study 50 h

Lecturers: G. Orzechowski (WUT)

Objectives:
The goal of the class is to present neural networks as tools for pattern classification, function approximation, and system modeling and prediction. Neural methodology will be thus treated as a step in development of dynamic systems. Neural networks are presented as static or dynamic systems whose main distinctive properties are modularity and adaptability. They are presented in the context of classification, function approximation, dynamical system modeling, and other applications.

Contents:
Classification abilities are discussed for contemporary versions of Rosenblatt's perceptron, support vector machines, and multi-layer perceptrons. They are complemented with elements of learning theory and probably approximately correct estimators. Approximation properties of neural networks are outlined for multilayer perceptrons and for radial basis function networks, and connected to linear regression models. In particular, approximation quality and generalization problems are discussed. Back-propagation is derived as an effective way to calculate gradients in large systems. Theoretical abilities of function approximation properties of multi-layer perceptrons and radial basis function networks are also analyzed. Dynamic neural networks are outlined in the context of dynamical system modeling, contents-addressable memories, and combinatorial system optimization. Neural ARMA models will be derived as a generalization of ARMA models, and their properties will be analyzed. Stability of dynamic networks is discussed in the context of system optimization and contents-addressable memories.

Practical Work: Exercises on the application of the neural networks

A1.2 the second semester modules

Group project			
Credits: 5 Semester 2 **Compulsory: Yes**			
Format	Lectures 15	Examples	Private study 120 h
Lecturers: Various local staff			

Objectives: The aim of this module is to provide students with the opportunity to apply their specialized knowledge to the solution of a real problem, and gain practical experience of the processes involved in the team-based design and testing of a robotic system.

Work contents: The projects contain a mix of theoretical and practical work. The practical work may consist of one or more of the following components: software development, simulation, hardware development. The deliverables always include a report and, if requested by the supervisor(s), software and/or hardware deliverables.

Examples of project subjects given in previous years:

- Hybrid localization system for a mobile robot using magnet detection.
- Modeling, Identification and Control of 3 DOF Quanser Helicoptor.
- Comparison of various temperature control laws.
- Development of models for camera calibration and validation.
- Calibration of the geometric parameters of the Neuromate robot.
- Trajectory planning for pick and place operations: application to the Orthoglide.
- Measurement of reaction forces during the walking of Nao
- Motion estimation for visual odometry.
- Representing environmental sounds using auditory cortical models.
- Scheduling of fixed priority tasks for uni-processor systems.
- Robust control of an overhead crane. Development of a signal processing tool for maximum entropy reconstruction of 2D NMR spectra

Abilities: Each individual student will be expected to have contributed fully in the team's activities, and will be expected to be able to:

Justify the hardware and software design of their team's finished robot.
Use project management tools to organise their activities.
Produce, test, and evaluate a working system.
Deliver appropriate documentation of a professional standard.

Assessment: The evaluation is made by a jury which includes the supervisor(s) plus at least two other staff members. It is based on the following items: quality of work, quality of the written report, and final defense in front of the jury. The supervisors can also require a demonstration of the final product. The effectiveness of the team's management of the project, and the understanding and contribution of each team member are also taken into account.

Recommended texts: Will be given by the lecturers.

Mechanical design methods in robotics

Credits: 5 Semester 2
Compulsory: No

Format	Lectures 25 h	Supervised project 15 h	Private study 85 h

Lecturers: K. MIANOWSKI (WUT), S. CARO (ECN), D. CHABLAT (ECN), D. ZLATANOV (UNIGE), M. ZOPPI (UNIGE), C. VILA (UJI)

Objectives: This course presents the overview of the design process – specification, conceptual design, product design. The students will learn basic principles of industrial robot design.

Contents:
The following subjects will be discussed:
- Conceptual design: concept generation, concept evaluation.
- Product design: documentation, product generation, evaluation for function and performance, evaluation for cost, ease of assembly and other measures.
- Computer aids for mechanical design. CAD/CAE/CAM systems.
- The design of robotic production cell.
- Fundamentals of integrated design of control and drive systems taking into account measurement, gearing and transmission systems.
- Design of a serial robot manipulator (using CAD).

Practical Work: CAD design of manipulator.

Abilities: After completing this course, the students will be able to:
- Design a serial robotic manipulator.
- Formulate properly the needed information for conceptual design (requirements),
- Use CAD systems on the basic level for the design of typical mechanism (serial arm),
- Elaborate the design on general level without material, drive systems and actuators consideration,
- Provide the conceptual documentation for the arm design.

Assessment: 30% continuous assessment, 70% from end of semester examination.

Recommended texts:
- K.C.Gupta, *Mechanics and Control of Robots*, Springer 1997
- J.E.Shigley, J.J.Uicker, *Theory of Machines and Mechanisms,* McGraw Hill 1995.

Further readings: CAD software documentation

Mobile robots

Credits: 5 Semester 2
Compulsory: No

Format	Lectures 24 h	Tutorials 16	Private study 68 h

Lecturers: P. MARTINET (ECN), G. GARCIA (ECN), R. ZACCARIA (UNIGE), W. SZYNKIEWICZ (WUT), J. SALES (UJI)

Objectives: This course presents fundamentals of wheeled mobile robots modelling, control and localization.

Contents: The following subjects will be addressed:

Non holonomic constraint equations,
Classification of robots, using the degrees of mobility and steering,
Posture kinematic model,
Configuration kinematic model,
Motorisation of wheels.
Dynamic models including the contact model,
Trajectory generation,
Controllability and stabilisation, static and dynamic feedback linearization, nonlinear control based on Lyapunov.
Relative localisation: odometry, inertial systems.
Absolute localisation: GPS, sensor fusion,
3D range measurements and goniometry.
Analysis of the observability of robot location.
Path planning

Practical Work: The students will program mobile robots to follow some prescribed trajectories and to implement control laws taking into account the Cartesian localization.

Abilities: After completing this course, the students will be able to:

Generate the motion trajectories considering the robot constraints,
Simulate the robot motion,
Implement suitable control strategy,
Choose an appropriate localization system for a mobile robot,
Design and implement localization systems using various state observers

Assessment: 30% continuous assessment, 70% from end of semester examination.

Recommended texts:

- C.Canudas, B. Siciliano, G.Bastin (editors), *Theory of Robot Control*, Springer-Verlag, 1996. (chapters 7,8, and 9)
- Ch. Ahikencheikh, A. Seireg, *Optimized-Motion Planning; Theory and Implementation*. John Wiley 1994.
- R.Siegwart I.R. Nourbakhsh, *Intrduction to Autonomous Mobile Robots*, MIT Press second edition 2010. B.Siciliano, O.Khatib,edt , *Robots Handbook*, Springer-Verlag 2008, Chapters 17, 34, 35.

Artificial intelligence			
Credits: 5 Semester 2 **Compulsory: No**			
Format	Lectures 24 h	Examples 16h	Private study 68 h
Lecturers: W. KASPRZAK (WUT), C. ZIELINSKI (WUT), A. TACCHELLA (UNIGE), E. MARTINEZ (UJI), R. ZACCARIA (UNIGE)			

Objectives:
The goal of the course is to present advanced issues of artificial intelligence from the perspective of a computerized autonomous agent

Contents:
The first part covers basic methods of artificial intelligence – the logic of knowledge representation, inference rules and problem solving including: uniformed search, informed search with heuristic functions, constraint satisfaction problems and adversarial games. The second part deals with practical planning and acting of an autonomous agent (i.e., situation space, plan space, plan decomposition, hierarchic decomposition, contingency planning), and with probabilistic reasoning. The third part discusses agent design problems in the area of knowledge acquisition (learning from observations, in neural networks and reinforcement learning), and machine perception (image and speech understanding).

Abilities: After completing this course, the students will be able to:

Produce and analyse the knowledge inference rules,

Acquire the knowledge using: active observation, neural networks processing.

Process the visual information and recognize speech using the machine perception.

Assessment: 30% continuous assessment, 70% from end-semester examination.

Recommended texts:
- S. Russell, P. Norvig, *Artificial Intelligence: A Modern Approach*. Prentice Hall, Upper Saddle River, N.J., 2002.
- Stefano Nolfi, Dario Floreano (2000), *Evolutionnary robotics*, MIT Press.
- S. Russell, P. Norvig, *Artificial Intelligence: A Modern Approach*. Prentice Hall, Upper Saddle River, N.J., 2002.*Problem Solving*, Addison Wesley, 1997.

Further readings:
- G.F. Luger, W.A. Stubblefield, *Artificial Intelligence. Structures and Strategies for Complex Problem Solving*, Addison Wesley, 1997
- J-P. Delahaye, *Formal Methods in Artificial Intelligence,* Oxford 1987

Optimisation techniques			
Credits: 5 Semester 2 **Compulsory: No**			
Format	Lectures 24 h	Tutorials / Projects 16	Private study 68 h
Lecturer: F. BENNIS (ECN), W. OGRYCZAK (WUT), C. NATTERO (UNIGE)			

Objectives: The lecture presents different theoretical and computational aspects of a wide range of optimization methods for solving a variety of problems in engineering and robotics.

Contents:

- Basic concepts of optimization,
- Gradient based methods,
- Evolutionary algorithms,
- Multi objective optimization methods,
- Robust optimization methods,
- Inverse problem,
- Multidisciplinary optimization problems,
- Programming aspects,

Practical Work: exercises on design and motion planning robotics problem.

Abilities: The students will be able to:

- Understand different theoretical and computational aspects of a wide range of optimization methods,
- Realize the possibilities offered by the different optimization methods,
- Use of optimization toolbox.

Assessment: 30% continuous assessment, 70% from end of semester examination.

Recommended texts:

R. Fletche, *Foundation of structural optimization.* A unified Approach, John Wiley & Sons, 1987.

Further readings: will be provided by lecturer

Nonlinear control

Credits: 5 Semester 2
Compulsory: No

Format	Lectures 24 h	Examples 16 h	Private study 68 h

Lecturers: F. PLESTAN, C. MOOG (LS2N)

Course objectives: The goal is to give the basis of modern nonlinear control theory. Analysis and control of nonlinear systems are considered using a so-called algebraic approach. Examples taken from robotics or electric drives demonstrate the feasibility of the methodology.

Contents:
- Introduction to the algebraic approach for nonlinear systems and its mathematical tools.
- Structural analysis, concepts of relative degree, of controllability and observability.
- Control methods: feedback linearization, decoupling, reference trajectory tracking.
- Lyapunov functions and their properties.
- Recursive global stabilization by state feedback of nonlinear systems.
- Design of a nonlinear observer. Special observability forms for input-affine systems.
- Observer-based stabilization. Methods to avoid finite-escape time.
- Dynamic output feedback semi-global stabilization.

Practical Work: Exercises, use of computer algebra, case study on an inverted pendulum.

Objectives: After completing this course, the students will be able to:
Understand the theoretical fondamentals on the control of nonlinear systems,
Apply advanced nonlinear control on a variety of robotics systems,
Implement control strategy, and calculate the corresponding observer.

Assessment: 30% continuous assessment, 70% from end-semester examination

Recommended texts:
- G. Conte, C.H. Moog and A.M. Perdon, *Algebraic Methods for Nonlinear Control Systems. Theory and Applications*, Springer-Verlag, 2006.
- A. Isidori, *Nonlinear Control Systems. 2nd edition*, Springer-Verlag, 1989.
- R. Marino and P. Tomei, *Nonlinear Control Design: Geometric, Adaptive and Robust*, Prentice Hall, 1995.

Further readings:
- M. Vidyasagar, *Nonlinear Systems Analysis*, Prentice Hall, 1993.

Robot Programming Methods

Credits: 5 Semester 2 **Compulsory:** Yes			
Format	Lectures 30h	Tutorials/Labs 30h	Private study 50 h
Lecturers: C. ZIELINSKI (WUT)			

Objectives: To learn the robot programming methods

Contents:
Several historic and currently used specialized robot-programming languages will be presented. Then focus will shift to robot programming frameworks, i.e.: libraries of modules, a pattern according to which they have to be assembled and tools for producing new modules. Robot will be treated as an embodied agent and its operation will be described formally in terms of transition functions. Both sequential and concurrent decompositions of those functions will be considered. Competitive and cooperative composition of results and the definition of complex behaviours will be the subject of presentation. The transition from synchronous to event driven systems will be shown. Deliberative vs. behavioural, fuzzy vs. crisp, deterministic vs. indeterministic systems will be described from the point of view of the definition of the transition functions governing their behaviour. Cooperation and coordination in multi-robot systems will be described. The course will also cover implementation issues, especially programming paradigms (procedural, object-oriented, component based). Error handling and debugging issues will also be explained. The presentation of implementation structures (methods of merging specialized languages and programming frameworks and the influence on the compilation/interpretation of the resulting code) will follow. An introduction to formal languages and how to build a simple compiler of a robot language will be shown. ROS and MRROC++ robot programming framework will be used for presenting examples of complex systems, e.g. capable of two-handed manipulation with force sensing, visual servoing, voice communication and capability to reason. The course will conclude with the description of software for swarms of autonomous robots and coordinated multi-robot systems requiring utility based task allocation.

Abilities:

After completing this course the students will be able to:

- To use the typical robot programming language,
- To elaborate his own robot programming framework for a single robot,
- To specify the programming framework for the multi-robot systems.

Software architectures for robotics

Credits: 5 Semester 2
Compulsory: No

Format	Lectures 16 h	Examples 30 h	Private study 68 h

Lecturers: Fulvio MASTROGIOVANNI (UNIGE) and G. GARCIA (ECN)

Course objectives: A robot is a multi-purpose, multi-form and multi-function machine. It exhibits completely new and unique characteristics with respect to what it is for, how it is structured and what it is able to do. In order to cope with this diversity in form and function, software architectures for robots must be grounded on top of a model enforcing flexibility and efficiency well beyond those developed in other domain applications.
Students will be able to identify stable requirements in different and various scenarios, common design issues and similar approaches to recurrent software development problems while designing new Robotics applications.
Another objective of the module is to make the students familiar with robotics middleware very commonly used in robotics applications, like ROS (Robot Operating System).

Contents:
The following topics will be considered:
- Trends in software development for robots.
- Software environments for robot programming.
- Component-based software frameworks.
- Communication and information flow.
- Management of heterogeneous hardware and software.
- Examples of available programming frameworks and architectures.
- ROS: Robot Operating System.
- Effibox.

Practical Work:
In the lab, the students will develop applications using ROS.

Abilities: After completing the course students will be able to:
- Choose an appropriate architecture and design framework for a given robotic system.
- Identify infrastructural and practical solutions for the problem at hand.
- Develop applications for fairly complex robotic systems using existing middleware.

Assessment: 50% continuous assessment, 50% from end-semester examination

Recommended texts:

- D. Brugali (Ed.). Software Engineering for Experimental Robotics. In Springer Tracts in Advanced Robotics, vol. 30. Springer Berlin / Heidelberg, 2007.
- I. Sommerville. Software Engineering. In the International Computer Science Series. Addison Wesley, 2000.

Embedded Systems			
Credits: 5 Semester 2 **Compulsory: No**			
Format	Lectures 30	Tutorials / Projects 15	Private study 68 h
Lecturer: S. DENEI (UNIGE)			

Objectives:
This course presents the fundamentals of embedded systems from both the architectural point of view and the basics of programming, with particular attention to sensing and actuating devices.

Contents:
- General overview of existing families of micro-controllers, DSPs, FPGAs, ASICs.
- Basics of developing for embedded systems: coding, compiling, linking, downloading, executing.
- Different kinds of memory devices and memory organization.
- On-chip and off-chip peripherals units and basic I/O operations: ADC, DAC, PWM, Parallel port, Counters, Timers.
- Buses and communication channels.
- Interrupt-driven programming.
- Fundamentals of real-time programming for embedded systems.

Practical Work:
Exercises will be set, which will involve design and implementation and testing of real-time code for micro-controllers

Annex 2. Syllabus of the second year modules

A1.1 The third semester modules at ECN

French Language		
Credits: 4 Semester 3 (ECN) **Compulsory: Yes**		
Format	Lectures / Conversation 50 h	Private study 50 h
Lecturers: ECN Language department		
Objectives: Allow the student to achieve a sufficient oral and written comprehension of the local language of the hosting country. As well as an introduction to country culture. **Organization:** The language will be offered in 2 options: Beginners (joint group with 1st semester students), Advanced (for those who have a previous experience in the language); **Contents:** Culture lectures, conversations, reading, and writing exercises		
Abilities: After completing this course: The students will be able to communicate, speak and write, everyday life requirements, The advanced group will be able also to read and write texts related to scientific topics.		
Assessment: 50% of the mark derived from a continuous evaluation, 50% from end of semester examination.		
Recommended texts: the texts will be given by lecturers.		

Remark: if the student is fluent in French, the French language course can be replaced by a scientific course of Emaro+ M2 or by one of the common courses of the French common track of ROBA2 which are given in French for instance (*Modèles et Systèmes* or *Optimisation Techniques*).

Research Methodology			
Credits: 5 Semester 3 (ECN) **Compulsory: Yes**			
Format	Lectures 15 h	Lab 3 h	Private study 70 h
Lecturer: I.Taralova (ECN)			

Objectives:

This course aims to provide the students with the necessary skills and tools to carry out and present a research topic. It presents the jobs of researchers and university staff, in research institutions, labs and in R&D departments in companies, and how to apply for them.
This course includes also the bibliographical study for the master thesis topic.

Contents:

- Setting goals and defining objectives of the master thesis;
- Bibliographical research and collecting information;
- Written communication: reports, theses, journal & conference papers;
- Oral communication: research presentations, attending conference & presenting a paper;
- Presentation of the researcher position, and university staff;
- The research institutions in EMARO+ countries;
- How to apply for a faculty position or research institutions in Europe and worldwide;
- Seminars will be organized to present the state of art of advanced topics.

Abilities: After completing this course, the students will be able to:

- Research the background and perform literature review relating to a specified subject;
- Identify key aspects of research work;
- Use a range of techniques to research and collect information;
- Demonstrate an understanding on how research may be evaluated;
- Plan and prepare a research proposal;
- Deliver a satisfactory written report, including correct citation of related works and analysis;
- Understanding the job of the researchers and faculty staff.

Assessment: Written report about related work of his research topic (50%), oral presentation (50%).

Recommended texts:

- J. Collis, R. Hussey, *Business Research A Practical Guide for Undergraduate and Postgraduate Students*, 2nd Edition, Basingstoke: Palgrave, 2003,
- M. Polonsky, D. Waller, *Designing and Managing a Research Project,* Sage, 2005

Sensor based control of complex robots

Credits: 4 Semester 3 **Compulsory: Yes**			
Format	Lectures 24 h	Examples, Laboratory 12 h	Private study 60 h
Lecturers: Ph. Martinet (ECN), O. Kermorgant (ECN)			

Objectives: This course presents the fundamentals of the modelling and control techniques used in sensor-based control of complex robots. By complex robots, we consider multi arms systems (including Humanoid robots), parallel robot. Topics will include classical kinematic and dynamic robot control (computed torque control) based expressed in joint, Cartesian and sensor space (i.e visual servoing) more generally. A special focus will be done on redundant robot control using task priority formalisms.

Contents:

The following subjects will be treated:

- Kinematic control of robots
- Computed torque control
- Position/Force control
- Sensor based control
- Vision based control (Interaction matrix, 2D, 3D, Hybrid)
- Advanced Vision based control (Omnidirectional, Fisheye, Vision/force, ...)
- Visual servoing applications (manipulators, mobile robots, aerial robots, parallel robots, humanoids ...)
- Point-based and region-based image moments
- Redundancy and task priority
- Unilateral contraints in sensor space (object visibility, obstacle avoidance)
- Multi points control of robots

Practical Work: Exercises will be set, which will involve modelling some visual features, and simulation of different control laws.

Abilities: After completing this course the students will be able to:

Understand the different properties of visual servoing scheme.

- Use the most convenient methods to obtain the required models,
- Understand practical applications of the mathematical modelling of kinematic visual features.

Assessment: 30% continuous assessment, 70% from end of semester examination.

Recommended texts:

- W. Khalil, E. Dombre: *Modeling, identification and control of robots*, Hermes Penton, London, 2002.
- F. Chaumette, S. Hutchinson,*Tutorial, Visual servo control PART I: Basic approaches,* IEEE Robotics and Automation Magazine, December 2006
- F. Chaumette, S. Hutchinson, *Tutorial, Visual servo control PART II: advanced approaches,* IEEE Robotics and Automation Magazine, March 2007
- Visual Control of Robots: High Performance Visual Servoing, P.I. Corke, Robotics and Mechatronics Series, 2, John Wiley & Sons Inc (November 1996), Language: English, ISBN: 0471969370
- O. Kanoun, F. Lamiraux, P.-B. Wieber, Kinematic control of redundant manipulators : generalizing the task-priority framework to inequality task, IEEE Trans. on Robotics, 2011

Advanced Modelling of Robots			
Credits: 5 Semester 3 (ECN) **Compulsory: Yes**			
Format	Lectures 24 h	Examples 16h	Private study 80 h
Lecturer: S. Briot (CNRS), S. Caro (CNRS)			

Objectives: This course presents advanced modelling techniques (geometric, kinematic and dynamic) of robots (tree structure robots, parallel robots, and hybrid robots) composed of rigid links.

Contents: The following topics are treated:

- Description of complex mechanical systems (tree-structured or closed loop systems),
- Geometric and kinematic models of closed-loop structure robots, constraints equations, mobility analysis, singularity analysis (introduction to DHm convention of tree-structured and closed loop systems)
- Workspace analysis of full-mobility and lower-mobility parallel robots
- Calibration of geometric parameters
- Recalls of dynamics principle (Newton-Euler, Euler-Lagrange, Principle of virtual works) for open and closed-loop mechanism systems
- Dynamic modelling of rigid tree-structure robots: the inverse and direct dynamic problems, the base inertial parameters, computation of the ground forces.
- Dynamic modelling of rigid parallel robots without and with actuation redundancy: the inverse and direct dynamic problems, the base inertial parameters, computation of the ground forces.
- Analysis of the degeneracy conditions of the dynamic model of rigid parallel robots, and singularity crossing
- Identification of dynamic parameters

Practical Work: Exercises will be set, involving modelling, identification and simulation of robots. Advanced technical papers from recent international conferences will be analysed and reviewed.

Abilities: After completing this course, the students will be able to:

- Understand the fundamentals of the mathematical models of robots and their applications in robot design, control and simulation.
- Analyse the mobility of parallel robots and understand the notion of operation modes
- Analyse, identify and illustrate the serial and parallel (including the constraint) singularities of parallel robots
- Identify the geometric and dynamic parameters of a robot
- Use of the best methods to develop the required models of a given architecture
- Apply the given techniques to other systems such as mobile robots or passenger cars
- Use the convenient numerical schemes for numerical integration.
- Use modelling, optimization, and signal processing tool boxes software packages (Matlab, Adams).

Assessment: 30% continuous assessments, 70% from end of semester examination.

Recommended texts:

- S. Caro, lecture notes on "*Geometric and Kinematic Modelling of Serial and Parallel Robots*"
- W. Khalil, E. Dombre, *Modelling, identification and control of robots*, Hermes Penton, London, 2002.
- J. Angeles, *Fundamentals of Robotic Mechanical Systems,* Springer-Verlag, New York, 3rd edition, 2007
- Merlet, J. P., 2006, Parallel Robots (Solid Mechanics and Its Applications), Springer, New York, Vol. 128.
- S. Briot, lecture notes on "Advanced Dynamic Modelling of Robots"
- S. Briot and W. Khalil, *Dynamics of Parallel Robots*, Springer.

Further readings: will be provided during the course

Humanoid Robots			
Credits: 4 Semester 3 (ECN) **Compulsory: No**			
Format	Lectures 20 h	Examples 12 h	Private study: 68 h
Lectures: C. Chevallereau (CNRS), Y. Aoustin (Univ. Nantes)			

Contents:

This course presents the fundamentals of control of humanoids for locomotion and manipulation. The students will learn the most common solutions used for stable motion synthesis and control.

The course contains the following items:

- biped locomotion: kinematics and dynamics, modelling of the contact with the ground
- motion synthesis for bipeds : optimization method, simplified models
- passive robots: properties, stability analysis (Poincaré map), extension
- control methods for postural stabilization, walking, and running : ZMP, on line adaptation, stability analysis, foot placement
- humanoid: whole motion control (redundancy)
- manipulation and grasping
- under-actuated hand

Practical Work:

Exercises will be set, which will involve modelling biped, definition of optimal motion, simulation of passive robots, experiments on under-actuated hand.

Objectives:

After completing this course, the students will be able to:

define the walking robot stability considering the static and dynamic condition,
define a control law for a walking robot,
analyse the stability of a control strategy,
synthesize and implement the motion of simple walking robot,
define a control law for a manipulation task

Assessment: 30% continuous assessment, 70% from end of semester examination

Recommended texts:

- C. Chevallereau, G. Bessonnet, G. Abba et Y. Aoustin *Bipedal Robots*, ISTE Wiley, CAM Control Systems, Robotics and Manufacturing Series,
- E. R. Westervelt, J. W. Grizzle, C. Chevallereau, J-H Choi, *Feedback Control of Dynamic Bipedal Robot Locomotion, and Benjamin Morris*, Taylor & Francis/CRC Press, 2007.
- M. Vukobratovic, B. Borovac, D. Surla, D. Stokic, *Biped Locomotion: Dynamics, Stability, Control and Application*, Springer-Verlag , 1990.
- Marc Raibert , *Legged Robots That Balance*, MIT Press, 2000

Further readings:

will be provided during the course

Optimal kinematic design of robots			
Credits: 4 Semester 3 (ECN) **Compulsory: No**			
Format	Lectures 20 h	Examples 12 h	Private study 68 h
Lectures: P. WENGER (CNRS)			

Objectives:

This course presents advance tools and methodologies for the kinematic design of new robots. Both serial and parallel kinematic architectures will be treated. The students will learn how to manage a general kinematic design problem in robotics.

Contents:

The course contains the following items:

- Formalization of relevant criteria for the performance evaluation of robots (accessibility, feasibility of trajectories, dexterity, cuspidality…),
- Methods for the calculation of robot workspace and of the maximal regions of feasible trajectories, taking into account joint limits and obstacles,
- Classification of cuspidal robots (non-singular posture changing robots) and geometric conditions for a robot to be cuspidal/noncuspidal
- Optimal design and placement of serial-type robots in cluttered environments,
- Methods for designing parallel kinematic robots (architecture design, geometric design, coping with singularities and operation modes),
- Application examples in typical industrial cases,
- Application examples for the design of innovative robots.

Abilities:

After completing this course the students will be able to:

- Set an optimal design problem in robotics, taking into account multi-objective criteria,
- Evaluate the kinematic performances of serial and parallel robots,
- Know how to design a cuspidal or a non-cuspidal robot
- Find the best suitable robot for a given task
- Find the best placement of the robot's base,
- Design parallel kinematic robots with given mobility and motion type.

Assessment: 30% continuous assessment, 70% from end of semester examination.

Practical Work:

Exercises will be set, which will involve the optimal kinematic design of typical robotic manipulators (serial and parallel). Simulation and verification using Robotic-CAD systems.

Recommended texts:

- J. Angeles, *Fundamentals of Robotic Mechanical Systems,* Springer-Verlag, New York, 2002,
- P. Wenger : "Performance Analysis of Robots", in *Robot Manipulators: Modeling, Performance Analysis and Control*, E.Dombre, W.Khalil (ed.), ISTE, London, 2006.

Further readings:

- J.P. Merlet, *Parallel Robots*, Second Edition, Springer, 2006.

Autonomous Vehicles			
Credits: 4 Semester 3 **Compulsory: No**			
Format	Lectures 20 h	Examples, Laboratory 12 h	Private study 60 h
Lecturers: P. MARTINET (ECN), E. LECARPENTIER (ECN), C. LAUGIER (Inria)			

Objectives: This course presents the fundamentals of the perception for intelligent and autonomous vehicles. Topics will include Mapping, Decision making process, autonomous navigation and platooning.

Contents: The following subjects will be treated:

- Introduction to IV and ITS application
- Bayesian framework
- Decision process
- SLAM
- Autonomous navigation (ADAS, IPAS)
- Platooning

Practical Work: Exercises will be set, which will involve platoon of autonomous vehicle, SLAM, Bayesian framework and decision process

Abilities: After completing this course the students will be able to:

- Have an overview of an intelligent vehicles capabilities
- Estimate the risk and the situation
- Put in place a decision making process
- Understand the global architecture of an autonomous vehicle and platoon

Assessment: 30% continuous assessment, 70% from end of semester examination.

Recommended texts:

- **Eskandarian** Azim, Handbook of Intelligent Vehicles, Springer London Ltd Edition, 2012, 1630 pages, ISBN-10: 0857290843, ISBN-13: 978-0857290847
- **Cheng** Hong, Autonomous Intelligent Vehicles, Theory, Algorithms, and Implementation, Series: Advances in Computer Vision and Pattern Recognition, Springer, 2011, 147 pages, ISBN:978-1-4471-2279-1
- Yaobin Chen, Lingxi Li, Advances in Intelligent Vehicles, 1st Edition, Academic Press, Dec 2013, 336 Pages, ISBN : 9780123971999
- Multiple View Geometry in Computer Vision, Richard Hartley, Andrew Zisserman, Barnes&Nobles, 2nd edition 2004, ISBN-10: 0521540518
- Three-Dimensional Computer Vision, Olivier Faugeras, MIT Press, November 1993, ISBN: 0262061589
- An invitation to 3D vision: from images to geometric models, Yi Ma, Stefano Soatto, Jana Kosecka, S. Shankar Sastry, Springer, 2010, ISBN-10: 1441918469, ISBN-13: 9781441918468
- Visual Odometry, Part I - The First 30 Years and Fundamentals, Scaramuzza, D., Fraundorfer, F., IEEE Robotics and Automation Magazine, Volume 18, issue 4, 2011.
- Visual Odometry: Part II - Matching, Robustness, and Applications, Fraundorfer, F., Scaramuzza, D., IEEE Robotics and Automation Magazine, Volume 19, issue 1, 2012
- Simultaneous localization and mapping: part I, Durrant-Whyte, H. ; Australian Centre for Field Robotics, Sydney Univ., NSW ; Bailey, Tim, IEEE Robotics & Automation Magazine, 3(2):99-110, June 2006
- Simultaneous localization and mapping (SLAM): part II, Bailey, Tim ; Australian Centre for Field Robotics, Sydney Univ., NSW ; Durrant-Whyte, H., IEEE Robotics & Automation Magazine, 13(3) : 108 -117, Sept. 2006

From human motion to humanoid control			
Credits: 4 Semester 3 (ECN) **Compulsory: No**			
Format	Lectures 20 h	Examples 12 h	Private study 68 h
Lecturers: S. SAKKA (ECN)			

Objectives: This course makes a review of the necessary steps allowing a software simulation of a captured human motion to control a humanoid robot. It presents the fundamental knowledge on the mechanics of the human body considered as open kinematic chains of rigid bodies.

Contents:

The following subjects will be discussed:

- Human kinematics and dynamics modelling from non-invasive measures
  - Non invasive measurement of human movement, experimental process
  - Experimental, hardware and software artefacts
  - Musculo-skeletal system
  - Human models for robotics applications, approximations
  - Simulation of human dynamics from optical motion capture
- Imitation of human motion using a humanoid robot
  - Kinematics – application to manipulation, upper and whole body movements
  - Dynamics – application to whole-body humanoid motion generation
  - Autonomous behaviors

Abilities: After completing this course, the students will be able to:

- Measure human motion using optical motion capture system
- Model and simulate human dynamics
- Imitate hand, arm and whole body human motion (kinematics) using a humanoid robotic system
- Understand the security and ethics issues of interacting with human beings

Assessment: 30% continuous assessment, 70% from end of semester examination.

Recommended texts:

- W. Khalil, E. Dombre: *Modeling, identification and control of robots*, Hermes Penton, London, 2002.
- S. Kajita, H. Hirukawa, K. Harada, K. Yokoi: *Introduction à la commande des robots humanoïdes*, Springer, 2009.

Further readings:

will be provided by lecturers

Advanced Visual Geometry			
Credits: 4 Semester 3 **Compulsory:** yes			
Format	Lectures 20 h	Examples, Laboratory 12 h	Private study 68 h
Lecturers: O. KERMORGANT (ECN), D. MARQUEZ GAMEZ (IRT Jules Verne)			

Objectives: This course presents the fundamentals of the advanced vision-based perception algorithms. Vision is one of the most promising senses to be used in robotics, providing important geometrical information on the surroundings of the robot. In this way, two-view geometry extended to multiple-view geometry will be investigated in order to address the difficult problems of relative pose estimation, 3D registration, pose and velocity estimation, and Simultaneous Localization And Mapping. Depth cameras will also be introduced as they are more and more used in robot perception.

Contents: The following subjects will be treated:

- Projective geometry
- Epipolar geometry (Homography, Essential and fundamental matrix)
- Multi view geometry
- Visual odometry
- Pose and velocity estimation
- 3D registration
- Visual SLAM (Mono, stereo)
- RGB-D cameras

Practical Work: Exercises will be set, which will involve pose and velocity estimation, visual odometry, visual SLAM, RGB-D cameras

Abilities: After completing this course the students will be able to:

- Understand what can be done from visual geometry
- Develop algorithms for visual odometry
- Develop algorithm for SLAM application
- Perform 3D registration

Assessment: 30% continuous assessment, 70% from end of semester examination.

Recommended texts:

1. Multiple View Geometry in Computer Vision, Richard Hartley, Andrew Zisserman, Barnes&Nobles, 2nd edition 2004, ISBN-10: 0521540518
2. Three-Dimensional Computer Vision, Olivier Faugeras, MIT Press, November 1993, ISBN: 0262061589
3. An invitation to 3D vision: from images to geometric models, Yi Ma, Stefano Soatto, Jana Kosecka, S. Shankar Sastry, Springer, 2010, ISBN-10: 1441918469, ISBN-13: 9781441918468
4. Visual Odometry, Part I - The First 30 Years and Fundamentals, Scaramuzza, D., Fraundorfer, F., IEEE Robotics and Automation Magazine, Volume 18, issue 4, 2011.
5. Visual Odometry: Part II - Matching, Robustness, and Applications, Fraundorfer, F., Scaramuzza, D., IEEE Robotics and Automation Magazine, Volume 19, issue 1, 2012
6. Simultaneous localization and mapping: part I, Durrant-Whyte, H. ; Australian Centre for Field Robotics, Sydney Univ., NSW ; Bailey, Tim, IEEE Robotics & Automation Magazine, 3(2):99-110, June 2006
7. Simultaneous localization and mapping (SLAM): part II, Bailey, Tim ; Australian Centre for Field Robotics, Sydney Univ., NSW ; Durrant-Whyte, H., IEEE Robotics & Automation Magazine, 13(3) : 108 -117, Sept. 2006

A1.2 The third semester modules at UJI

Research Methodology			
Credits: 6 Semester 3 (UJI) **Compulsory: Yes**			
Format	Lectures 10 h	Examples 0 h	Private study 140 h
Lecturers: R. BERLANGA, G. QUINTANA			

Objectives: This course is intended to provide the student with the necessary skills and tools to carry out and present a research topic. This course is considered also as the background study and collect information part for the master thesis topic, which will be completed during the fourth semester.

Contents:

- Research methodology,
- Written communication: reports, theses, Journal & Conference papers,
- Oral communication: Research Presentations, Attending Conference & Presenting paper,
- Setting goals and defining objectives of the thesis.

Spanish Language		
Credits: 4 Semester 3 **Compulsory: Yes**		
Format	Lectures/ Conversation 50h	Private study 50 h
Lecturers: E. PORTALÉS, J. MARTÍ		

Objectives: The language courses will be offered in different levels from A1 (Beginners) to C2 according to the parameters defined in the Common European Framework of Reference for Modern Languages of European Council.
Students will be evaluated in a initials tests, classes (max 25 people) will be formed according to the test results.

Contents:
Culture lectures, conversations, reading, and writing exercises

Robotic Intelligence			
Credits: 5 Semester 3 (UJI) **Compulsory: Yes**			
Format	Lectures 30 h	Examples 15 h	Private study 80 h
Lecturer: A. PASCUAL DEL POBIL			

Objectives: Introduction to the topic of Machine Intelligence, understood as part of artificial intelligence that deals with those aspects of intelligence related to physical systems that interact in the real world. This intelligent behavior includes objectives such as: adaptation to a changing environment, active perception to interact with a partially unknown environment, explore, to learn, etc.

Contents:

- The study of intelligence. Fundamentals and panoramic
- Robot intelligence: the basics
- Neural networks for adaptive behavior
- Braitenberg vehicles and arquitetura of Subsumption
- Development: from locomotion to cognition
- Evolution, genetic algorithms and self-organizing
- Design principles of autonomous robots

Practical Work: **Laboratory exercises on modelling and development of intelligent systems**

Perception and Manipulation			
Credits: 4 Semester 3 (UJI) **Compulsory: Yes**			
Format	Lectures 30 h	Examples 10 h	Private study 85 h
Lecturer: Pedro J. SANZ			

Objectives:

This course is an indispensable piece of connection between robotic systems and the real world, where physical interaction is crucial. The way we interact with the universe surrounding a robot, is strongly influenced by the ability of perception of the environment implemented in it. Thus, during the physical interaction related to the ability to manipulate their environment, the robot may incorporate more robust and efficient resources to the extent that it is capable to combine different types of sensory information from different perceptual channels. We show that the combination of vision, force / torque and tactile feedback, is a powerful mechanism to attack complex problems of robotics, handling impossible to solve properly this multi-sensorial without cooperation.

Contents: The following subjects will be treated:

- Introduction to Artificial Perception.
- Perception-Action Integration.
- Gripping and Handling Robotics.
- Autonomous vs. teleoperated manipulation
- Introducing Learning Tasks grip.
- Sensory Fusion Technical Information in the Context of Robotic Grasp.
- Case Study-1: Jaume, the Robot Assistant UJI.
- Case Study-2: Towards Autonomous Intervention Underwater Robotics

Cooperative Robotics			
Credits: 5 Semester 3 (UJI) **Compulsory: No**			
Format	Lectures 30 h	Examples 10 h	Private study 85 h
Lecturer: E. CERVERA			

Objectives: The distribution of devices, sensors and actuators, among several mobile robots increases flexibility and robustness, and reduces the overall cost compared to monolithic solutions based on a single gifted robot. However, for efficient cooperation among a team of robots, it is necessary to address and solve challenges to efficiently manage devices and communications between them. They also represent a test for the allocation and planning of real tasks. Its applications range from exploration and / or efficient surveillance environments, to the work of rescue assistance.

Contents:

- The following subjects will be treated:
- Introduction to cooperative robotics
- Latest robotic technology network (EEE Technical Committee on "Network Robotics"
- Literature review of some significant articles in the field of cooperative robotics.
- Technology for cooperative robotics: (Zigbee, Wifi, etc..) and software (T Las Vegas, etc..),
- Architectures and software platfc cooperative robotics.
- Design of platforms for cooperative app
- Examples of these platforms can be Jad Stage, or ROS.

Practical Work: laboratory: multi-agent systems

Cognitive Processes			
Credits: 4 Semester 3 (UJI) **Compulsory: No**			
Format	Lectures 30 h	Examples 15 h	Private study 80 h
Lecturer: L. MUSEROS			

Objectives: The development of robotics has been directed toward the development of skills in robots, similar to those of human beings, regardless of the cognitive processes underlying human intelligent behavior. Probably the poor implementation of natural cognitive processes to robotics and artificial intelligence is because neuroscience, the discipline that should nurture knowledge on natural cognitive processes, has not been able so far to provide a generic explanation of behavior of our brain, which could be used for artificial intelligence and robotics. This course will approach the study of the latest discoveries in neuroscience of human brain function, and then move to the implementation of artificial cognitive processes.

Contents:

- Use of cognitive processes modeling world
- Cognitive computer vision, and sensory integration
- Construction of cognitive maps
- Cognitive processes of action
- Case study: autonomous navigation of robots
- Cognitive processes of interaction
- Modeling of artificial emotional intelligence
- Cognitive learning

Practical Work: Exercises will be set, which will involve preparing and presenting a paper in scientific format.

Ambient Intelligence			
Credits: 5 Semester 3 (UJI) **Compulsory: No**			
Format	Lectures 30 h	Tutorials 5 h, Lab.10h	Private study 80 h
Lecturer: José V. MARTÍ			

Objectives: The goal of the course is to enable students to understand the Ambient Intelligence computing paradigm, which envisions a world where people (and possibly robots) are surrounded by intelligent sensors/actuators and interfaces embedded in the everyday objects around them.

Contents:
The following subjects will be discussed:
Middleware Infrastructures for Ambient Intelligence
Networks of sensors and actuators
Robots within Smart Environments
User/Situation Modelling and Context Awareness
Human-centred adaptive interfaces, Augmented Reality and wearable computing
Applications: from Smart Dust to Smart Cities

Practical Work: Laboratory exercises with the KnowHouse simulator.

Telerobotics			
Credits: 4 Semester 3 (UJI) **Compulsory: No**			
Format	Lectures 30 h	Tutorials 5 h, Lab.10h	Private study 80 h
Lecturer: R. MARÍN			

Objectives: The overall goal of this course is to study the processes and tools to design systems of remote control for electromechanical devices. The evolution of information technologies and communications research opens new possibilities with interesting applications in improving the methods and industrial and civil processes. Device control through communication networks, and more specifically the Internet public network, is currently an emerging and very productive line of research, which also has a great interest in the industry. Still there are very few via Web robotic systems that allow remote control of electro - mechanical devices in industrial scopes and / or research. As an illustrative example, the first Internet robot (The Mercury Project) was designed and implemented in late 1995 at the University of Berkeley. Since then, the interest of the international scientific community in these systems has grown exponentially thanks in part to the very rapid evolution of features that are experiencing telecommunication and also the benefits of these remote control systems in terms of the possibility of the operator to be located anywhere in the terrestrial globe.

Contents: The following subjects will be discussed:
Networked Robots.
Telerobotics.
Tools for remote control.
Multi-Device Network Architectures.
User Interfaces for remote control.
The communication network and its influence on the remote
Applications of remote control in the social and industrial do

Practical Work: Laboratory exercises with the KnowHouse simulator.

A1.3 The third semester modules at WUT

Polish Language		
Credits: 4 Semester 3 (WUT) **Compulsory: Yes**		
Format	Lectures / Conversation: 50 h	Private study 50 h
Lecturer: WUT language department		
Objectives: Allow the student to achieve a sufficient oral and written comprehension of the local language of the hosting country. As well as an introduction to country culture. **Organization:** The language will be offered in 2 options: Beginners (joint group with 1st semester students), Advancers (for those who have a previous experience in the language); **Contents:** Culture lectures, conversations, reading, and writing exercises		

Research methodology			
Credits: 6 Semester 3 (WUT) **Compulsory: Yes**			
Format	Lectures 15 h	Seminar 10 h	Private study 120 h
Lecturers: T. Zielinska, C. Zielinski			
Objectives: This course is intended to provide the student with the necessary skills and tools to carry out and present a research topic. It presents the profession of university staff, researchers in research institutions, and in R&D departments in enterprises and how to apply for them. This course includes also the beginning of the bibliographical study and collect information part for the PhD thesis topic. **Contents:** Setting goals and defining objectives of the thesis; Bibliographical research and collect of information; Written communication: reports, theses, journal & conference papers; Oral communication: research presentations, attending conference & presenting a paper; Presentation of the profession of researchers, and university staff; The research institutions in EMARO+ countries; How to apply for a faculty position or research institutions in Europe; Seminars will be organized to present the state of art of advanced topics.			

Biomechanics			
Credits: 5 Semester 3 (WUT) **Compulsory: Yes**			
Format	Lectures 30h	Tutorials: 15 h	Private study 85 h
Lecturers: K. Kedzior, C. Rzymkowski (WUT)			
Objectives: This course presents the fundamental knowledge on the mechanics of the human body considering the skeleton and muscular system. The students will learn how to analyse static and dynamic forces and torques acting on the body parts during motion and in working conditions. **Contents:** The following subjects will be discussed: • fundamentals of the human body anatomy, • biomechanical analysis of human motion			

- skeletal muscles control,
- structure, action, energy sources, power and efficiency of skeletal muscles,
- cooperation between muscles,
- biomechanics of bone tissue,
- anthropometry,
- human motion properties,

system,

- kinematics of the human body,
- introduction to dynamical analysis of the human body,
- fundamentals of occupational biomechanics,
- medical biomechanics – prosthesis and exoskeletons,
- biomechanics of impacts/trauma biomechanics.

Practical Work:

- laboratory work, e.g EMG signals measurement and analysis;
- numerical exercises, e.g. kinematic and kinetic analysis of human gait (based on force plate and cinematographic experimental data), estimation of injury risk to the human musculo-skeletal system under impact loads;
- student presentation (~20 minutes) and preparation of a short report (~10-15 pages) on any topic (related to biomechanics), proposed by the student.

Bio-robotics

Credits: 5 Semester 3 (WUT)
Compulsory: No

Format	Lectures 30h	Project /lab. 15h	Private study 85 h

Lecturers: T. Zielinska (WUT)

Objectives:
This course presents the fundamentals of bio-inspired robotics. The topics include the biological motion properties, motion planning and biological sensors. It will be presented how the knowledge of biological motion properties is transformed into robotics. The aim of the course is to insipre creativity for novel robotic concepts by introducing recent challenges and biologicaly based solutions.

Contents: The following subjects will be discussed:

- historical background,
- motion properties of simple animals and their body build
- motion properties of complex animals and their body build,
- summary of biological motion principles
- robotics motion rules using biological inspirations,
- architectures of control systems and its reference to the neuro-biological control
- design solutions inspired by biology,
- discussion of the autonomy and adaptability observed in living world and autonomy obtained in robotics,
- humanoida, walking machines
- novel robotic systems
- guided project on biologically inspired motion synthesis of mobile robots or on the novel kinematic structures of autonomous moving robots.

Practical Work: includes project elaboration using real mobile robots or professional design software.

Dynamics of multi-body systems

Credits: 5 Semester 3 (WUT)
Compulsory: No

Format	Lectures 30h	Tutorial/project 15 h	Private study 85 h

Lecturers: J. Frączek, M. Wojtyra (WUT)

Objectives:

To learn the advanced mechanical systems dynamics and the methods of analysis of multibody mechanical systems. These systems consist of many components, thus create complex mechanisms for which classical kinematics and dynamics methods are not applicable. The gained knowledge is useful for complex systems design together with analysis of its dynamical properties.

Contents: The following subjects will be discussed:

Description of multi-body systems using different types of coordinates.
Constraints: systematic formulation of constraint equations; detection and elimination of redundant constraints.
Kinematic analysis: constraint Jacobian matrix, numerical methods used for multi-body systems analysis.
Assembling of a multi-body mechanism, detection of singular configurations.
Newton-Euler and Lagrange equations of motion for complex multi-body systems,
Direct and inverse dynamics problems for multi-body systems: formulation and methods of solving; numerical integration of ODE and DAE.
Exercises devoted to kinematics and dynamics of various mechanisms – analyses conducted using a widely used multibody package (ADAMS).

Practical Work: analysis of a given mechanical system using ADAMS package, building a simple multi-body kinematics solver in MATLAB.

Advanced mechanical design

Credits: 5 Semester 3 (WUT)
Compulsory: No

Format	Lectures 30 h	Examples/project 15 h	Private study 85 h

Lecturers: K. Mianowski (WUT)

Objectives:
This course presents the design methods for complete complex, precise mechanical structures. The students will learn how to design the mechanical structure together with mounting of actuators, driving systems, localisation of supply cables, controllers etc.

Contents: The following subjects will be treated:

Serial and parallel manipulators – difference in the requirements stated in the design
Introduction to material science,
Driving elements: their types and performances,
Analysis of mechanical efficiency in mechanical systems considering mechanical resistance (*i.e.* friction) and limited efficiency of driving system and actuators,
Actuating systems, specification of required motor power considering the designed robotics system, its mechanical efficiency and working conditions,
Design procedure using material science (material choice with material strength analysis) and including driving system, actuators, power supply, etc.
Examples considering robots for cardio-surgery, walking machines, mobile robots.

A1.3 The third semester modules at UNIGE

In UNIGE the modules are designed to give the students the necessary knowledge to carry out the master thesis in the fields of:

- Intelligent / Service / Cooperative Robotics
- Factories of the Future / Industrial Robots and Mechanical Design of New Robot Structures
- Human-Robot Interaction /Ambient Intelligence
- Perception / Manipulation

Italian Language		
Credits: 4 Semester 3 **Compulsory: Yes**		
Format	Lectures/ Conversation 50h	Private study 50 h
Lectures: UNIGE language department		
Objectives: The language courses will be offered in different levels from A1 (Beginners) to C2 according to the parameters defined in the Common European Framework of Reference for Modern Languages of European Council. Students will be evaluated in a initials tests, classes (max 25 people) will be formed according to the test results. **Contents:** Culture lectures, conversations, reading, and writing exercises		

Research Methodology			
Credits: 6 Semester 3 (UNIGE) **Compulsory: Yes**			
Format	Lectures 15 h	Seminars 10 h	Private study 120 h
Lectures: all staff			
Objectives: This course is intended to provide the student with the necessary skills and tools to carry out and present a research topic. It is considered also as the background study and collects information part for the master thesis topic, which will be completed during the fourth semester. **Contents:** It covers: Research methodology, Written communication: reports, theses, Journal & Conference papers, Oral communication: Research Presentations, Attending Conference & Presenting paper, Setting goals and defining objectives of the thesis.			

Flexible automation			
Credits: 4 Semester 3 UNIGE **Compulsory: No**			
Format	Lectures 30 h	Examples 10 h	Private study 85 h
Lecturers: M. Zoppi, D. Zlatanov			
Objectives: This course presents a general intersectorial description of the industrial automation scopes, of the involved means and methods, and of the socio-economical issues related with the domain. The scope, to be achieved, covers the definition of the scenario, into which the competencies need be enhanced with designing and			

developing the different topics of the industrial intelligent automation techniques.

Contents: The following subjects will be treated:

- Automation terminology.
- Concepts of simultaneous engineering: product and process design.
- Mechatronics means: machines, robots, handling and transportation equipment.
- System control, process and machine diagnostics, information and communication.
- Design concepts and tools.
- Simulation, Virtual Manufacturing and Rapid prototyping.
- Enterprise strategies for automation and for flexibility.
- Life cycle engineering and management. Environmentally responsible manufacturing.
- Example cases will be discussed.

Practical Work: **laboratory**

Advanced Modelling and Control of Robotic Structures

Credits: 4 Semester 3 UNIGE

Compulsory: Yes

Format	Lectures 24 h	Examples 16h	Private study 80 h

Lecturers: G. Casalino, M. Zoppi, M. Baglietto, A. Turetta

Objectives:

The course formerly generalizes the modelling techniques (Geometric, Kinematic and Dynamic) to robotic structures more complex than simpler cascade ones (e.g. branched, open/close and parallel connections) with extension to cases of presence of flexible links. Then it will be shown how the developed methods can be used for calibration, simulation, kinematic/dynamic/interaction control, parametric identification and adaptive control of such more general robotic structures.

Contents:

Geometric and kinematic modelling: constraints equations, mobility analysis, singularity analysis. Fundamentals of screw theory and its application to modelling, design and calibration

Dynamic modelling: principle of virtual work, Lagrangian formulations, Newton-Euler formulation.

Simulation: inverse and direct dynamic problems; use of Lagrangian formulation; use of Newton-Euler formulation; evaluation of constraints reaction force-torques.

Kinematic/dynamic/interaction control: the overall two layered functional architecture; the upper-lying kinematic control layer and relevant algorithmic structures; underlying dynamic/interaction control layer and relevant algorithmic structures, conditions for control robustness

Parametric identification: least-squ recursive techniques, Lyapunov basec within fully and partially sensorizec conditions of persistency of identifiability

Adaptive control: certainty-equivaler based techniques and Lyapunov basec Fundamentals of Modelling and si flexible structures: flexible joints shaping; modal analysis and fini analysis, generalized Newton-Euler Identification and control aspects structures

Practical Work: Exercises will be set, involving modelling, simulation, identification and control of complex structure robots. Advanced technical papers from recent international conferences will be analysed and reviewed.

Ambient Intelligence

Credits: 4 Semester 3 (UNIGE)

Compulsory: No

Format	Lectures 30 h	Tutorials 5 h, Lab.10h	Private study 80 h

Lectures: A. Sgorbissa, F. Mastrogiovanni

Objectives:

The goal of the course is to enable students to understand the Ambient Intelligence computing paradigm, which envisions a world where people (and possibly robots) are surrounded by intelligent sensors/actuators and interfaces embedded in the everyday objects around them.

Contents: The following subjects will be discussed:

- Middleware Infrastructures for Ambient Intelligence.
- Networks of sensors and actuators.
- Robots within Smart Environments.
- User/Situation Modelling and Context Awareness.
- Human-centred adaptive interfaces, Augmente and wearable computing.
- Applications: from Smart Dust to Smart Cities.

Practical Work: Laboratory exercises with the KnowHouse simulator.

Distributive Robotics

Credits: 4 **Semester:** 3
Compulsory: No

Format	Lectures: 30 h	Examples: 18 h	Private study: 102 h

Lectures: G. CASALINO, A. SGORBISSA

Objectives:
Different robotic agents can be employed for achieving a set of (possibly shared) objectives via the cooperative activities. Applications of this concept ranges from the employment of teams of autonomous sensorized vehicles for distributed exploration, patrolling, monitoring, surveying, etc., to cooperating multi-mobile manipulators (each one possibly multi-arm) employed for manipulating, transporting and assembling or dismantling, large structures within constructions, rescue operations, post-disaster intervention, etc.; with a recent tendency to be proposed also for the factory or yards environments. Aspects of cooperation can be even identified within complex modular articulated chains, whenever their composing parts are viewed as a set of simpler robot agents, all together cooperating in executing the commanded tasks by part of the resulting more complex structure.
As a matter of fact the possibility for an adequate information exchange among the robot agents (either of explicit type - like cable, radio, or acoustic links -, or even of implicit type - like mutual vision and/or mutual physical interactions) and the availability of adequate (obviously distributed) cooperative control algorithms, represent the two fundamental features underlying any cooperative multi-individual-robot organization.
Accordingly with the above considerations, the main objective of the course will be that of exploiting the evidenced commonality of basic features for presenting the Cooperative robotic within an underlying unifying conceptual, methodological and algorithmic framework. In particular, while developing the framework, it will be also evidenced how the additional feature of having the each robot-agent capable of localizing itself (absolutely or ego-centrally within the team) will it also play an essential role.

Contents: The topics below will be developed with respect to ground, aerial, as well as underwater scenarios.

- Robot explicit communication networks (models, technologies and algorithms) and implicit communication means (extraction of task-significant information from mutual vision and/or interaction)
- Cooperative localization, mapping and navigation within multi-mobile robot agents.
- Coordination control techniques for teams of autonomous vehicles.
- Example applications: distributed sampling, patrolling, surveying, exploration.
- Coordination control techniques for multi-mobile manipulators.
- Example applications: assembly and construction, post-disaster intervention.
- Modular robotic structures
- Modular components and technologies
- Self-configurable, self-organizing structures.
- Example applications: industrial and space applications.

Machine Learning

Credits: 4 **Semester:** 3
Compulsory: No

Format	Lectures: 30 h	Tutorials: 18 h	Private study: 102 h

Lecturers: S. Rovetta, A. Verri

Objectives:
The goal of the class is to present Artificial Neural Networks and other well known Machine Learning techniques (e. g. Gaussian Processes, Bayesian Learning, hidden Markov models, etc.) as systems for solving supervised and unsupervised learning problems, with a specific emphasis on Robotics applications. Such learning systems can be applied to pattern recognition, function approximation, time-series prediction and clustering problems. Some mention will be made to the use of ANNs as static systems for information coding, and dynamical systems for optimization and identification.

Contents: The course will cover the following topics.

- Classification and identification for contemporary versions of Rosenblatt's Perceptron, Multi-Layer Perceptrons, Support Vector Machines and other Kernel Methods, and multi-layer perceptrons.
- Approximation properties of neural networks for multilayer perceptrons and for radial basis function networks.
- Insights on Machine Learning and Statistical Learning Theory: in particular, approximation quality and generalization problems.
-
- Learning algorithms like Back-propaga Sequential Minimal Optimization t unconstrained and constrained opt problems. Practical learning examp discussed applied to Robotics.
- Neural ARMA models are derive generalization of ARMA models, a properties analysed.

Practical Work:
Exercises on the application of architectures and learning algorithms to Robotics domains.

Modular Robotics for Future Factories

Credits: 4 **Semester:** 3
Compulsory: No

Format	Lectures: 30 h	Examples: 18 h	Private study: 102 h

Lecturers: G. Cannata, (G. Casalino)

Objectives: It is currently widely recognized that a future much larger diffusion of robots for manufacturing will be achieved once the robotic research and development activities will have fully addressed the needs of SME manufacturers; which can be roughly summarized as follows: Cost effectiveness at low lot sizes, Intuitive to be used, Easily adaptable to a wide variety of application tasks, Easily reconfigurable kinematic structure, whenever needed. With the last three of the above points to be moreover operated by non-specialized personnel. In this perspective it is also recognized that a substantial answer to the mentioned needs should relay on the development of modularly configurable robotic structures, which should also exhibit motion self-organizing properties, once assembled.in the desired configuration. Still in the mentioned perspective, the present course is therefore intended for providing the students with the fundamental mechatronic concepts and related technologies enabling the the realization of reconfigurable modular robotic structures; as well as the internally distributed (within the automatically connected computational units resulting from the assembly) self-organizing control methods and related algorithms.

Contents:
- Mechanical modular technology (joints-links
- Embedded/modular actuation technology
- local joint control algorithmic units units
- Distributed self-organizing control algorithm

- Embedded/modular proprioceptive sensing technology (position, velocity, joint torque sensors) - Modular exteroceptive technologies (force/torque/tactile concentrated and distributed sensing) - Embedded/modular processing units - Embedded internal networking	distributed computational structures. - Distributed internal diagnostic and fault tolerance - Self-configuring and self-assembly structures - Foreseeable future factory application examples - Extension to foreseeable future space applications

Annex 3. Assessment rules

1. STRUCTURE OF EMARO+

EMARO+ consists of two years:

First year, denoted **M1**, contains taught modules (Semesters 1 and 2, denoted **S1** and **S2**).

Second year, denoted **M2**, contains taught modules (semester 3, denoted **S3**) and research dissertation (semester 4, denoted **S4**).

The first year is taught **simultaneously** in **ECN**, **WUT** and **UG**. Students study commonly agreed modules, totalling **60 ECTS**, which are examined jointly. During the third semester, more specialised modules are proposed. The programme of this semester is different in the four institutions.

During the first three semesters, students **must accumulate 30 ECTS** for each semester by passing each module at **60% of the maximum mark** or above to progress.

The **fourth semester** consists of an assessment of the students' **research thesis** (**30 ECTS**).

Examination Boards, nominated by the management committee of EMARO+, will be held at the end of each semester to determine students' progression to the subsequent semester(s). Students who validate the four semesters will be **awarded** the **two master degrees of the institutions where they studied**.

The Partner Institutions shall provide academic and personal support to the students and shall assign a personal mentor for each student.

2. GENERAL PRINCIPLES

2.1 Institutions shall inform students, by means of a handbook and/or EMARO+ website, of the means by which modules shall be assessed and the method of reassessment for redeeming a failure.

2.2 Methods of assessment, which involve observation, interaction and oral elements, and in particular the dissertation (thesis) element of the degree, shall not be subject to anonymity.

2.3 Examining Boards shall be presented with all marks of assessment undertaken during the concerned semester(s). Marks for modules shall be recorded out of a hundred according to the marking criteria in 3 below.

2.4 Resit (taking an exam again) marks must be clearly identified in the presentation of marks to the Examining Board.

2.5 All results will be disclosed to students electronically after the formal Examination Boards.

3. MARKING CRITERIA

Due to the collaborative nature of EMARO+, the consortium is committed to the ECTS grading structure. Examinations and assessments will be marked out of a hundred. The marks equate to ECTS grades as given in Tables 1 and 2.

Table 1: Statiscal ECTS grading scale policy

ECTS Grade	Description	% of successful students
A	**Excellent** - outstanding performance with only minor errors	10%
B	**Very Good** - above the average standard but with some errors	25%
C	**Good** - generally sound work with a number of notable errors	30%
D	**Satisfactory** - fair but with significant shortcomings	25%
E	**Sufficient** - performance meets the minimum criteria	10%
FX	**Fail** - some more work required before the credit can be awarded	0%
F	**Fail** - considerable further work is required	0%

Table 2: Correspondence of letters convention with marks between 0 and 100.

ECTS Grade	A	B	C	D	E	F/FX
Mark	100- 90	89-80	79- 70	69- 65	64- 60	59 or less

Late submission of assessed work shall result in a mark of 0 being awarded and a decision of fail being recorded, unless an extension has been granted prior to the deadline.

4. MODULE RULES

4.1 Modules shall be assessed individually, as prescribed by the relevant institution(s). The assessment method of a module may take the form of an unseen written examination paper, set projects or other course work assignments.

4.2 In addition to satisfying the assessment requirements of a module, each student must satisfy the attendance requirements. It is the responsibility of Institutions to monitor satisfactory attendance and assessment in each module. Students who do not satisfy the attendance and assessment requirements of a module will be reported to the appropriate committee in the partner institution concerned.

4.3 A mark will be assigned to each student, based on his/her performance.

4.4 The Pass mark for modules will be set at 60. Credits will be awarded to candidates who pass a module. All modules pursued must be passed. (However, see 4.5 below).

4.5 Late submission of assessed work shall result in a mark of 0 being awarded and a decision of fail being recorded, unless an extension has been granted prior to the deadline.

5. PROGRESSION RULES

An examination committee shall be held at the end of each semester to determine whether or not students qualify to validate the semester.

5.1 Students must obtain a mark of 60 or better to validate a module.

5.2 Students must accumulate 30 ECTS credits to validate a semester.

5.3 Students who fail a module(s), at the discretion of the Examination committee, will normally be permitted one further attempt at the second session examination. This session will take place at the end of M1 for the S1 and S2 modules, and will take place at the end of S3 for the modules of S3. No second session is foreseen for S4. See section 7 regarding the marking policy for redeemed modules.

5.4 Students who are eligible to progress to the next semester shall not be allowed to repeat any module for which credit has been awarded in order to improve their performance.

5.5 Students will be permitted to proceed from S1 to S2 whatever their results. Students must complete M1 successfully for being permitted to proceed to M2. This means that they must accumulate 30 ECTS credits during the modules of S1 and 30 ECTS credits during the modules of S2.

5.6 Students who are repeating failed modules and who fail to qualify to proceed to the next year at the second attempt will be informed that they have failed EMARO+ scheme.

5.7 Students who fail to a semester have the right of appeal in accordance with the appeals procedure adopted by the Consortium Board of Studies.

6. THESIS RULES (4th semester)

6.1 A principal supervisor will be appointed for each candidate who will be responsible for ensuring that studies are carried out in line with the institution's good practice guidelines. A second supervisor from the first year institution will also be appointed. In case of mobility during S4 the main advisor will be from the hosting institution the second advisor will be nominated from the second institution.

6.2 The student should submit three typed copies and one electronic copy of the dissertation to the Exam Co-ordinator, in the format prescribed by the examination committee and notified to the student by the institution at which the dissertation takes place. The student should also submit another copy to each member of the jury committee.

6.3 Dissertations submitted for examination shall normally be openly available unless security classification or restriction of access has been approved, on a case by case basis, by the Examination committee. However, Examination committee may restrict photocopying of and/or access to a dissertation for a specified period of up to five years. It shall be the responsibility of the candidate's supervisor to make an application to the examination committee at least one month before the defence.

6.4 A candidate is at liberty to publish the whole or part of the dissertation work produced prior to its submission. The supervisors must approve such published work.

6.5 Retention and disposal of a dissertation shall be in accordance with the policy of the awarding institution.

6.6 In all institutions the Dissertation will be examined by an examiners committee composed of the student's supervisors and at least two another staff members. The examination includes an oral presentation of about 35 minutes. The mark must reflect the quality of work (60%), quality of writing report (20%), and quality of oral presentation (20%).

6.7 A candidate who fails to submit the dissertation by the deadline specified for Emaro+, and who has not been granted an extension of candidature due to special circumstances will fail the degree.

7 FINAL AWARD

7.1 At the end of each Semester, the Examination Committee will be held to determine award decisions on students pursuing EMARO+.

7.2 Appeals against award decisions shall be considered in accordance with the appeals procedures adopted by the Examination committee, and administered by the partner institution concerned in conjunction with their own awarding institutional regulations.

7.3 At the end of the second year successful students will be awarded a double Masters degree from the first and second institutions where they studied.

7.4 Degrees will be awarded according to national assessment structures, namely, for France, based on the average of M1 and M2 results: *Très Bien* (90-100), *Bien* (80-89), *Assez bien* (70-79), *Passable* (60-70) and *Echoué*.

7.5 The original diploma will be delivered around April of the year after the graduation. The following certificates will be delivered before the original diploma to help the student looking for a job or Ph.D. position:

a- Transcripts of M2, including the second year marks and grade. The validation of the master "Automatique, Robotique et Informatique Appliquée", speciality: "Robotique Avancée" will be indicated if the semesters S3 and S4 are validated.

b- Certificate of success including the result of the master based on the average of the four semesters.

c- Diploma supplement (will be delivered with the original diploma).

8. REDEEMING A FAILURE

8.1 Students who fail a module in S1 or S2 will fail to progress from M1 to M2 and shall, at the discretion of the Examination committee, normally be permitted one further attempt during the second session (at the end of the second semester) to redeem their failure in each such module. The mark for this further attempt shall be up to the capped threshold of 60 in each such module.

8.2 As regards students who fail a module, the Examination Committee has the discretion to allow a student to:

a. be re-examined in the module as a whole (mark capped at 60); or

b. be re-examined in those parts of the module which he/she has failed where more than one piece of work contributes towards the final module mark (mark capped at 60);

c. be re-examined without any restriction on mark. This would only be allowed where the student has demonstrated special circumstances to the Committee. See section 9.

8.3 Students must not expect, as of right that they will be allowed to redeem failures, allowed to repeat failed modules or be allowed to continue. The Examination committee may take into account other circumstances relating to the candidate's case, such as attendance and performance in classes, before taking any progression decision.

8.4 A candidate who is to be re-examined in set projects or other forms of course assessment could be required to submit for examination new work on different topics from his/her original work, which originally failed to satisfy the examiners.

8.5 Candidates who are attempting to redeem a failure and who fail on the second attempt, will be informed that they have failed EMARO+.

8.6 Candidates who pass the failed modules and accumulate at least 60 ECTS credits during M1 qualify to proceed to the M2.

8.7 Candidates who pass the failed modules and accumulate at least 30 ECTS credits during S3 qualify to proceed to the S4.

9. EXCEPTIONAL CIRCUMSTANCES

9.1 In the case of illness or other exceptional circumstances, the Examination committee may grant an extension to the submission date or permit a supplementary examination to be held as appropriate. It is recognised that the marks of such students will not be subject to the ceiling of 60. They will be considered as 'First Sit' students, which means that they will be marked according to the same grading scale as students who attempt the examinations/ course work for the first time.

9.2 Students who miss a submission deadline/ are absent from an examination or who fail a piece of coursework or an examination due to illness or other exceptional circumstances should notify the course leader at the institution in which they are studying before the examination or deadline for submission or, if this is not possible, as soon after the examination/ deadline as is possible and before the date of the examination board. To be considered as a 'First Sit' candidate the student will need to provide written evidence (for example medical certificates) to the Board.

9.3 The time limit for the completion of the degree may be extended in exceptional cases only. A reasoned application, supported by appropriate independent evidence, must be submitted by the candidate to the Examination committee, and any appropriate institutional academic committees.

Requests for an extension shall be considered with reference to the following criteria:

a- Normally, suspensions / extensions will be granted only in cases of illness, serious domestic difficulties or exceptional commitments, which can be demonstrated to have adversely affected the candidate. A full and reasoned case, supported by appropriate, satisfactory, medical or other independent evidence, and a work-plan for completion of the thesis within the extension requested, must be made by the department for consideration by the Examination committee.

b- In cases which arise as a result of illness:

i- Satisfactory medical or other relevant documentary evidence must be supplied. (The extent and nature of the illness as described in the certificate are invaluable in assessing the case.)

ii- A clear statement must be supplied, showing that the institution concerned has evaluated the situation in which the candidate finds himself / herself as a result of the illness and that it considers the requested extension to be appropriate for completion in accordance with the work-plan.

10. UNFAIR PRACTICE

10.1 Students must ensure that they do not engage in any form of unfair practice, whereby they take action which may result in them obtaining for themselves or others, an unpermitted advantage.

10.2 Unfair practice is defined as any act whereby a person may obtain for himself/herself or for another, an unpermitted advantage. An action shall be considered to fall within this definition whether occurring during, or in relation to, a formal examination, a piece of coursework, or any form of assessment undertaken in pursuit of EMARO+.

10.2.1 Examples of unfair practice in examination conditions are as follows:
a- introducing into an examination room any unauthorised form of materials such as a book, manuscript, data or loose papers, information obtained via an electronic device such as a programmable calculator, pager, mobile phone, or any source of unauthorised information;
b- copying from or communicating with any other person in the examination room, except as authorised by an invigilator;
c- communicating electronically with any other person;
d- impersonating an examination candidate or allowing oneself to be impersonated;
e- presenting evidence of special circumstances to examination boards which is false or falsified or which in any way misleads or could mislead examination boards;
f- presenting an examination script as your own work when the script includes material produced by unauthorised means. This includes plagiarism.

10.2.2 Examples of unfair practice in non-examination conditions are as follows:
a- Plagiarism. Plagiarism can be defined as using without acknowledgment another person's work and submitting it for assessment as though it were one's own work, for instance, through copying or unacknowledged paraphrasing (see 6.2.3 below);
b- Collusion. Collusion can be defined as involving two or more students working together, without prior authorisation from the academic member of staff concerned (e.g Programme leader, lecturer etc) to produce the same or similar piece of work and then attempting to present this work entirely as their own. Collusion may also involve one student submitting the work of another with the knowledge of the originator.
c- Falsification of the results of laboratory, field-work or other forms of data collection and analysis.

10.2.3 Examples of plagiarism are as follows:
- use of any quotation(s) from the published or unpublished work of other persons which have not been clearly identified as such by being placed in quotation marks and acknowledged;
- summarising another person's ideas, judgements, figures, software or diagrams without reference to that person in the text and the source in the bibliography;
- use of the services of "ghost writing" agencies in the preparation of assessed work;
- use of unacknowledged material downloaded from the Internet.

10.3 Students suspected of having engaged in unfair practice or assisting another student to engage in unfair practice, either in coursework or examination will be subject to the unfair practice procedures at the institution in which they are studying.

10.4 Institutions will investigate any cases of unfair practice identified at their institution, by means of their usual procedures and inform the Consortium of their results.

10.5 Students accused of engaging in unfair practice will be given an opportunity either in writing or person to present their case.

10.6 Students found guilty of unfair practice will be subject to the following penalties:
a- the issue of a written reprimand to the candidate, a record of the reprimand should be kept;
b- the text to be ignored when marking, resulting in a reduced mark;
c- the cancellation of the candidate's marks for the assignment;
d- the cancellation of the candidate's mark in the module concerned;
e- the cancellation of the candidate's mark in the module concerned and the preclusion of redeeming the failure until the next academic session;
f- the cancellation of the candidate's marks in all of the modules for the particular level of study;
g- the cancellation of the candidate's mark in all of the modules for the particular level of study and the disqualification of the candidate from any future Consortium examination;
h- In the event of an Institution deciding that the above penalties are inappropriate, the Institution may use its discretion to decide upon an appropriate penalty.

10.7 Students have the right of appeal, against substantiated allegations of Unfair Practice, in accordance with the appeals procedure adopted by the Consortium Management committee.

11. Defence procedure and related documents

Students must follow procedures indicated in each institution to prepare and present bibliographic and thesis report. Organization can be adapted according to local rules and obligations. Every student will be informed about those adjustments.

12. Attendance policy

The student must attend the whole Master programme. The partner institution is responsible for checking the attendance of the students.

- In case of non-attendance to the course, the local coordinator calls the student to understand the situation. The local coordinator informs the coordinator and the management committee which takes a decision on the actions to be taken depending on the reason of the extended absence.

- In case of non-attendance to the examinations that the student cannot justify with medical certificates or for which permission has not been given by the local coordinator of EMARO+, the student will be allowed to retake the exams, if he still does not show up, he will score 0.

13. Transferring schemes, suspending and withdrawing policy

- Transferring schemes: students are assigned a mobility scheme in accordance with their choices and with the Management Committee decision. Once, this scheme is accepted by the student, no change will be accepted, except in case of force majeure. The requests are discussed by the Management Committee and derogation can be given depending on the reason of the student.

- In case of suspending, the student has to transmit the reason for the suspending with all the supporting documents to the local coordinator within a period of five days after the beginning of the absence. The validity of the decision is left to the judgement of the academic jury semester.

- In case of withdrawing, the student has to inform the local coordinator within five days by email. The student has to be in line with administrative aspects of the programme and fees, no official document will be deliver before.

14. Disciplinary

In case of disciplinary issue, the local coordinator informs the coordinator and the management committee which takes a decision on the actions to be taken depending on the situation.

15. Complaint and appeal against non-academic decisions

In case of complaint or appeal against non-academic decisions, the student shall address his request to the local coordinator who informs the coordinator and the management committee. The final decision is taken by the management committee.