Study plan

Name of study plan: Cybernetics and Robotics - Senzors and Instrumention

Faculty/Institute/Others: Faculty of Electrical Engineering

Department:

Branch of study guaranteed by the department: Welcome page

Garantor of the study branch:

Program of study: Cybernetics and Robotics Type of study: Follow-up master full-time

Required credits: 98

Elective courses credits: 22 Sum of credits in the plan: 120

Note on the plan:

Name of the block: Compulsory courses in the program

Minimal number of credits of the block: 66

The role of the block: P

Code of the group: 2015_MKYRDIP Name of the group: Diploma Thesis

Requirement credits in the group: In this group you have to gain 30 credits Requirement courses in the group: In this group you have to complete 1 course

Credits in the group: 30 Note on the group:

Code	Name of the course / Name of the group of courses (in case of groups of courses the list of codes of their members) Tutors, authors and guarantors (gar.)	Completion	Credits	Scope	Semester	Role
BDIP30	Diploma Thesis	Z	30	22s	L	Р

Characteristics of the courses of this group of Study Plan: Code=2015_MKYRDIP Name=Diploma Thesis

BDIP30 Diploma Thesis Z 30
Independent final comprehensive work for the Master's degree study programme. A student will choose a topic from a range of topics related to his or her branch of study, which will be specified by branch department or branch departments. The diploma thesis will be defended in front of the board of examiners for the comprehensive final examination.

Code of the group: 2015_MKYRP

Name of the group: Compulsory subjects of the programme

Autonomous Robotics

Requirement credits in the group: In this group you have to gain 36 credits

Requirement courses in the group: In this group you have to complete 5 courses

Credits in the group: 36

Note on the group:

B3M33ARO

riole on the g	Toup.					
Code	Name of the course / Name of the group of courses (in case of groups of courses the list of codes of their members) Tutors, authors and guarantors (gar.)	Completion	Credits	Scope	Semester	Role
B3M33ARO	Autonomous Robotics	Z,ZK	7	3P+2L	L	Р
B3M38DIT	Diagnostics and Testing	Z,ZK	7	3P+2L	L	Р
B3MPVT	Tomáš Drábek	KZ	6	0P+4S	L	Р
B3MPROJ8	Project Petr Pošík, Drahomíra Hejtmanová, Martin Hlinovský, Jaroslava Mat jková, Tomáš Svohoda, Martin Šinoš Jana Zichová	Z	8	0p+6s	Z	Р

Characteristics of the courses of this group of Study Plan: Code=2015_MKYRP Name=Compulsory subjects of the programme

		-,	1	- 1
The Autonomous robotic	s course will explain the principles needed to develop algorithms for intelligent mobile robots such as algorithms for: (1) Mar	ping and localiza	ation (SLAM)	
sensors calibration (lidar	or camera). (2) Planning the path in the existing map or planning the exploration in a partially unknown map and performing the	ne plan in the wor	Id. IMPORTAN	Т:
It is assumed that studen	ts of this course have a working knowledge of optimization (Gauss-Newton method, Levenberg Marquardt method, full Newto	n method), mathe	ematical analys	is
(gradient, Jacobian, Hes	sian), linear algebra (least-squares method), probability theory (multivariate gaussian probability), statistics (maximum likelit	nood and maximu	ım aposteriori	
estimate), python progra	mming and machine learning algorithms.			

Z.ZK

B3M38DIT	Diagnostics and Testing	Z,ZK	7				
B3MPVT		KZ	6				
Teamwork is the basis of	of most of the activities that people perform in companies and their personal lives. In this course, students can try how to solv	e a technical task	in a team, how				
to cooperate, how to co	to cooperate, how to communicate together and how to solve problems such as project delays, how to include external influences in the plan, etc.						
B3MPROJ8	Project	Z	8				

Name of the block: Compulsory courses of the specialization

Minimal number of credits of the block: 26

The role of the block: PO

Code of the group: 2015_MKYRPO2

Name of the group: Compulsory subjects of the branch

Requirement credits in the group: In this group you have to gain 26 credits

Requirement courses in the group: In this group you have to complete 5 courses

Credits in the group: 26 Note on the group:

Code	Name of the course / Name of the group of courses (in case of groups of courses the list of codes of their members) Tutors, authors and guarantors (gar.)	Completion	Credits	Scope	Semester	Role
B3M38MSE	Modern Sensors	Z,ZK	6	2P+2L	Z	PO
B3M38SPD	Data Acquisition and Transfer	Z,ZK	6	2P+2L	Z	PO
B3M38VBM	Videometry and Contactless Measurement	Z,ZK	6	2P+2L	Z	PO
B3M38VIN	Virtual Instrumentation	Z,ZK	6	2P+2L	L	PO
B3M38ZDS	Analog Signal Processing and Digitalization	Z,ZK	6	2P+2L	Z	PO

Characteristics of the courses of this group of Study Plan: Code=2015_MKYRPO2 Name=Compulsory subjects of the branch

B3M38MSE	Modern Sensors	Z,ZK	6					
An overview of sensors	An overview of sensors of physical quantities used in industry and in research and methods of signal processing.							
B3M38SPD	Data Acquisition and Transfer	Z,ZK	6					
The aim of the course is	to acquaint students with principles and limits of data transmission from sensors and similar sources of information for IoT ar	nd M2M, wireless	sensor networks					
and specific algorithms,	respecting the limiting conditions of their function. The basic algorithms of distributed information processing in sensor networks	orks, as well as te	chnology for					
energy harvesting for po	owering the wireless nodes of the network, will be studied.							
B3M38VBM	Videometry and Contactless Measurement	Z,ZK	6					
This course focuses on	CCD and CMOS video sensors, and optoelectronic sensors in general and their use in contactless videometric measurement	systems. Further	optical radiation,					
its features, behavior an	d its use for acquiring object parameters, optical projection system, design of measurement cameras and processing of their	signal will be pres	sented. Students					
will design, realize and debug an independent project - 'Optoelectronic reflective sensor', during labs.								
B3M38VIN	Virtual Instrumentation	Z,ZK	6					
B3M38ZDS	Analog Signal Processing and Digitalization	Z,ZK	6					

Name of the block: Compulsory elective courses

Minimal number of credits of the block: 6

The role of the block: PV

Code of the group: 2015 MKYRPV2

Name of the group: Compulsory subjects of the programme

Aeronautical radio systems

Pavel Ková Pavel Ková (Gar.)

Requirement credits in the group: In this group you have to gain at least 6 credits (at most 90)

Requirement courses in the group: In this group you have to complete at least 1 course (at most 15)

Credits in the group: 6 Note on the group:

B3M37LRS

Name of the course / Name of the group of courses (in case of groups of courses the list of codes of their Code Completion Credits Scope Semester Role members) Tutors, authors and guarantors (gar.) **Dynamics and Control Networks** B3M35DRS Z,ZK 6 2P+2C Ζ Kristian Hengster-Movric Kristian Hengster-Movric **Integrated Avionics** L B3M38INA Z,ZK 2P+2L PV Martin Šipoš Space Engineering Kristian Hengster-Movric, Václav Navrátil, René Hudec, Martin Hrom ík, Martin B3M37KIN Ζ Z,ZK 6 2P+2L PV Urban, Petr Ondrá ek René Hudec René Hudec (Gar.)

Z,ZK

2P+2L

Ζ

B3M33MKR	Mobile and Collective Robotics	Z,ZK	6	2P+2L	Z	PV
B3M35NES	Nonlinear Systems and Chaos Kristian Hengster-Movric, Sergej elikovský Sergej elikovský Sergej elikovský (Gar.)	Z,ZK	6	2P+2C	Z	PV
B3M35OFD	Estimation, filtering and detection Vladimír Havlena Vladimír Havlena (Gar.)	Z,ZK	6	2P+2C	Z	PV
B3M35ORR	Optimal and Robust Control Zden k Hurák Zden k Hurák Zden k Hurák (Gar.)	Z,ZK	6	2P+2C	L	PV
B3M33PRO	Advanced robotics	Z,ZK	6	2P+2C	Z	PV
B3M35PSR	Real -Time Systems Programming Michal Sojka Michal Sojka Michal Sojka (Gar.)	Z,ZK	6	2P+2C	Z	PV
B3M33PIS	Industrial Information Systems	Z,ZK	6	2P+2C	Z	PV
B3M38PSL	Aircraft Avionics	Z,ZK	6	2P+2L	Z	PV
B3M35SRL	Flight Control Systems Martin Hrom ik Martin Hrom ik Martin Hrom ik (Gar.)	Z,ZK	6	2P+2L	Z	PV
B3M33UI	Artificial Intelligence Petr Pošík	Z,ZK	6	2P+2C	L	PV

Characteristics of the courses of this group of Study Plan: Code=2015_MKYRPV2 Name=Compulsory subjects of the programme B3M35DRS **Dvnamics and Control Networks** Z.ZK This course responds to an ever-increasing demand for understanding contemporary networks large-scale complex systems composed of many components and subsystems interconnected into a single distributed entity. Herein, we will consider fundamental similarities between diverse areas such as e.g. forecasting the spread of global pandemics, public opinion dynamics and manipulation of communities through social media, formation controls for unmanned vehicles, energy generation and distribution in power grids, etc. Understanding such compelling issues goes far beyond the boundaries of any single physical, technological or scientific domain. Therefore, we will analyze phenomena across different domains, involving societal, economic and biological networks. For such networked systems, the resulting behavior depends not only on the characteristics of their individual components and details of their physical or logical interactions, but also on a precise way those components are interconnected the detailed interconnection topology. For that reason, the first part of the course introduces fundamental theoretical and abstract computational network analysis concepts; in particular, the algebraic graph theory, network measures and metrics and fundamental network algorithms. The second part of the course subsequently views networks as dynamical systems, studies their properties and ways in which these are controlled, using mainly methods of automatic control theory. Integrated Avionics The course Integrated Modular Avionics (IMA) focuses on a modern concept of the approach to the development and design of aircraft electronics (avionics), where the transition from distributed HW systems to SW blocks. They use high-speed connections to exchange data in applications related to paid air transport. The existing regulatory basis and airspace sharing define the requirements for the accuracy, reliability, and functionality of electronic systems even in the event of a failure. In the course, students will learn details about the requirements for so-called safety-critical multi-sensor systems, methods of data processing from predetermined systems, fault detection methods, selection of primary computer and control system in parallel architectures, bus technology, and methods of testing/certification of aircraft instruments. B3M37KIN Space Engineering Z.ZK 6 The subject acquaints students with the basics of physics of the space environment and the technologies used in space systems, satellites, spacecrafts and launchers and methods used for the design and preparation of space missions. Subject matter includes a detailed description of the instrumentation of satellites and spacecrafts and its resistance to external influences of the space environment, and analysis of instruments and systems for spacecrafts and methods of their testing. It provides a basic overview of the trajectories of spacecrafts and their applications. The course also covers optoelectronics in space systems, sensors used, their modeling and description. It discusses the principles of underlying calculations, simulations and their processing. B3M37LRS Aeronautical radio systems Z.ZK 6 The course introduces students to the aeronautical radio engineering, aeronautical analogue, digital and satellite communication systems, aeronautical radio navigation including satellites navigation, primary secondary and passive radiolocation. The course gets students theoretical and practical knowledge of the operation of the aeronautical radio systems and their integration to the aircraft systems. B3M33MKR Mobile and Collective Robotics Z.ZK The course introduces a basic mobile robot structure design together with control methods aimed to achieve autonomous and collective behaviors for robots. Methods and tool s for data acquisition and processing are presented herein with the overall goal to resolve the task of autonomous navigation for mobile robots comprising the tasks of sensor fusion, environmental modeling including Simultaneous Localization And Mapping (SLAM) approaches. Besides sensor-processing related tasks, methods for robot trajectory planning will be introduced. The central topic of the course stands in specific usage of the afore methods capable of execution with groups of robots and taking the advantage of their cooperation and coordination in groups. Labs and seminars are organized in a form of an Open Laboratory whereas the students will implement some fundamental algorithms and study their properties on real data. B3M35NES Z.ZK Nonlinear Systems and Chaos The goal of this course is to introduce basics of the modern approaches to the theory and applications of nonlinear control. Fundamental difference when dealing with nonlinear systems control compared with linear case is that the state space approach prevails. Indeed, the frequency response approach is almost useless in nonlinear control. State space models are based mainly on ordinary differential equations, therefore, an introduction to solving these equations is part of the course. More importantly, the qualitative methods for ordinary differential equations will be presented, among them Lyapunov stability theory is crucial. More specifically, the focus will be on Lyapunov function method enabling to analyse stability of nonlinear systems, not only that of linear ones. Furthemore, stabilization desing methods will be studied in detail, among them the so-called control Lyapunov function concept and related backstepping method. Special stress will be, nevertheless, given by this course to introduce and study methods how to transform complex nonlinear models to simpler forms where more standard linear methods would be applicable. Such an approach is usually refered to as the so-called exact nonlinearity compensation. Contrary to the well-known approximate linearization this method does not ignore nonlinearities but compensates them up to the best possible extent. The course introduces some interesting case studies as well, e.g. the planar vertical take off and landing plane ("planar VTOL"), or a simple 2-dimensional model of the walking robot. Estimation, filtering and detection This course will cover description of the uncertainty of hidden variables (parameters and state of a dynamic system) using the probability language and methods for their estimation. Based on bayesian problem formulation principles of rational behavior under uncertainty will be analyzed and used to develop algorithms for parameter estimations (ARX models, Gaussian process regression), filtering (Kalman filter) and detection (likelihood ratio theory). We will demonstrate numerically robust implementation of the algorithms applicable in real life problems for the areas of industrial process control, robotics and avionics. B3M35ORR Optimal and Robust Control Z,ZK 6 B3M33PRO Advanced robotics Z.ZK We will explain and demonstrate techniques for modelling, analyzing and identifying robot kinematics. We will explain more advanced principles of the representation of motion in space and the robot descriptions suitable for identification of kinematic parameters from measured data. We will explain how to solve the inverse kinematic task of 6DOF serial manipulators

and how it can be used to identify its kinematic parameters. Theory will be demonstrated on simulated tasks and verified on a real industrial robot.

B3M35PSR Real -Time Systems Programming

z,zk

6

The goal of this course is to provide students with basic knowledge about software development for real-time systems, for example in control and embedded applications. The focus is on embedded systems equipped with a real-time operating system (RTOS). Lectures will cover real-time systems theory, which can be used to formally verify timing correctness of such systems. Another set of lectures will introduce methods and techniques used for development of safety-critical systems, whose failure may have catastrophic consequences. During labs, students will first solve a few simple tasks to familiarize themselves with basic components of VxWorks RTOS and to benchmark the used OS and hardware (Xilinx Zynq). The obtained metrics represent the typical criteria for assessing the suitability of a given platform for the given application. After the simple tasks, students will solve a complex task of time-critical motion control application which will require full utilization of RTOS features. All the tasks at the labs will be implemented in C (or C++) language.

B3M33PIS Industrial Information Systems

Z,ZK

6

The aim of this course is to provide students with the necessary set of skills essential for the design and management of modern production systems. In the first part of the course, the students will learn about methods of modeling and simulation of discrete production systems. Students will then gain insight into methods for data analysis to optimize the production as well as into methods for process mining. The final part of the course deals with methods of data and knowledge modeling, which are necessary for explicit capture and machine utilization of information and knowledge about production.

B3M38PSL Aircraft Avionics

Z.ZK

6

The subject is focused into a field of aircraft avionics including principles, sensors, measurement and evaluation systems and signal/data processing methods. The subject goes into details of studied systems, i.e. engine and aircraft monitoring systems, power systems, pressure-based systems, low-frequency navigation means, and flight recorders. The subject introduces currently used technology and methodology on aircraft and thus serves to understand fundamentals of avionics. Inertial navigation systems are discussed in more details as well as their aiding systems and sensors. The course focuses on both small and large aircraft as well as on UAV suited avionics.

B3M35SRL Flight Control Systems

Z,ZK

6

The course is devoted to classical and modern control design techniques for autopilots and flight control systems. Particular levels are discussed, starting with the dampers attitude angle stabilizers, to guidance and navigation systems. Next to the design itself, important aspects of aircraft modelling, both as a rigid body and considering flexibility of the structure, are discussed.

B3M33UI Artificial Intelligence

Z.ZK

6

The course deepens and enriches knowledge of Al gained in the bachelor course Cybernetics and Artificial Intelligence. Students will get an overview of other methods used in Al, and will get a hands-on experience with some of them. They will master other required abilities to build intelligent agents. By applying new models, they will reiterate the basic principles of machine learning, techniques to evaluate models, and methods for overfitting prevention. They will learn about planning and scheduling tasks, and about methods used to solve them. Student will also get ackquainted with the basics of probabilistic graphical models, Bayesian networks and Markov models, and will learn their applications. Part of the course will introduce students to the area of again populat neural networks, with an emphasis to new methods for deep learning.

Name of the block: Elective courses Minimal number of credits of the block: 0

The role of the block: V

Code of the group: 2015_MKYRH

Name of the group: Humanities subjects

Requirement credits in the group: Requirement courses in the group:

Theology

B0M16TE1

Credits in the group: 0 Note on the group:

Code	Name of the course / Name of the group of courses (in case of groups of courses the list of codes of their members) Tutors, authors and guarantors (gar.)	Completion	Credits	Scope	Semester	Role
B0M16FI2	Philosophy 2	Z,ZK	4	2P+2S	L	V
B0M16HT2	History of science and technology 2	Z,ZK	4	2P+2S	L	V
B0M16HSD	History of economy and social studies	Z,ZK	4	2P+2S	L	V
B0M16MPS	Psychology	Z,ZK	4	2P+2S	Z,L	V
A003TV	Physical Education Ji í Drnek	Z	2	0+2	L,Z	V
B0M16TE1	Theology	Z,ZK	4	2P+2S	L	V

Characteristics of the courses of this group of Study Plan: Code=2015_MKYRH Name=Humanities subjects

B0M16FI2	Philosophy 2	Z,ZK	4					
The course is oriented	The course is oriented on the transdisciplinar aspects of philosophy, informatics, physics, mathematics and biology.							
B0M16HT2	History of science and technology 2	Z,ZK	4					
This subject traces histo	rical developments in electrical engineering branches in the world and in the Czech Lands. Its ultimate goal is to stimulate s	tudents' interest ir	the history and					
traditions of the subject	, while highlighting the developments in technical education and professional organizations, the process of shaping scientific	life and the influe	nce of technical					
engineers								
B0M16HSD	History of economy and social studies	Z,ZK	4					
This subject deals with	the history of the European and Czech society in the 19th - 21th centuries. It follows the forming of the European and Czech	political represen	tation, its aims					
and achieved results as well as the social, economical, technical and cultural development and coexistence of the various ethnical groups.								
B0M16MPS	Psychology	Z,ZK	4					
A003TV	Physical Education	Z	2					

This subject provides to students the basic orientation in christian theology and requires no special previous education. After short philosophic lecture the basic theologic disciplines are gone through. The subject is determined not only to believer students who want to know the reliable theologic grounding but also above all to ones who want to get know Christianity - religion from which graws our civilization up.

Code of the group: MTV

Name of the group: Physical education

Requirement credits in the group: Requirement courses in the group:

Credits in the group: 0 Note on the group:

Code	Name of the course / Name of the group of courses (in case of groups of courses the list of codes of their members) Tutors, authors and guarantors (gar.)	Completion	Credits	Scope	Semester	Role
TVV	Physical education	Z	0	0+2	Z,L	V
TV-V1	Physical education	Z	1	0+2	Z,L	V
TVV0	Physical education	Z	0	0+2	Z,L	V
TVKZV	Physical Education Course	Z	0	7dní	Z	V
TVKLV	Physical Education Course	Z	0	7dní	L	V

Characteristics of the courses of this group of Study Plan: Code=MTV Name=Physical education

TVV	Physical education	Z	0
TV-V1	Physical education	Z	1
TVV0	Physical education	Z	0
TVKZV	Physical Education Course	Z	0
TVKLV	Physical Education Course	Z	0

Code of the group: 2015_MKYRVOL Name of the group: Elective subjects Requirement credits in the group: Requirement courses in the group:

Credits in the group: 0

Note on the group:

B3M33MKR

~Nabídku volitelných předmětů uspořádaných podle kateder najdete na webových stránkách http://www.fel.cvut.cz/cz/education/volitelne-predmety.html\\

Z.ZK

List of courses of this pass:

Code	Name of the course	Completion	Credits		
A003TV	Physical Education	Z	2		
B0M16FI2	Philosophy 2	Z,ZK	4		
	The course is oriented on the transdisciplinar aspects of philosophy, informatics, physics, mathematics and biology.	•			
B0M16HSD	History of economy and social studies	Z,ZK	4		
This subject deals	with the history of the European and Czech society in the 19th - 21th centuries. It follows the forming of the European and Czech po	litical representation	on, its aims		
	and achieved results as well as the social, economical, technical and cultural development and coexistence of the various ethnical	groups.			
B0M16HT2	History of science and technology 2	Z,ZK	4		
This subject traces	historical developments in electrical engineering branches in the world and in the Czech Lands. Its ultimate goal is to stimulate stude	ents' interest in the	history and		
traditions of the su	bject, while highlighting the developments in technical education and professional organizations, the process of shaping scientific life	and the influence	of technical		
	engineers				
B0M16MPS	Psychology	Z,ZK	4		
B0M16TE1	Theology	Z,ZK	4		
This subject provide	es to students the basic orientation in christian theology and requires no special previous education. After short philosophic lecture	he basic theologic	disciplines		
are gone through.	he subject is determined not only to believer students who want to know the reliable theologic grounding but also above all to ones wh	o want to get know	Christianity		
	 religion from which graws our civilization up. 				
B3M33ARO	Autonomous Robotics	Z,ZK	7		
The Autonomous	robotics course will explain the principles needed to develop algorithms for intelligent mobile robots such as algorithms for: (1) Mapp	ing and localization	n (SLAM)		
sensors calibration	(lidar or camera). (2) Planning the path in the existing map or planning the exploration in a partially unknown map and performing the p	olan in the world. IN	IPORTANT:		
It is assumed that s	It is assumed that students of this course have a working knowledge of optimization (Gauss-Newton method, Levenberg Marquardt method, full Newton method), mathematical analysis				
(gradient, Jacobia	(gradient, Jacobian, Hessian), linear algebra (least-squares method), probability theory (multivariate gaussian probability), statistics (maximum likelihood and maximum aposteriori				
	estimate), python programming and machine learning algorithms.				

The course introduces a basic mobile robot structure design together with control methods aimed to achieve autonomous and collective behaviors for robots. Methods and tool s for data acquisition and processing are presented herein with the overall goal to resolve the task of autonomous navigation for mobile robots comprising the tasks of sensor fusion, environmental modeling including Simultaneous Localization And Mapping (SLAM) approaches. Besides sensor-processing related tasks, methods for robot trajectory planning will be

Mobile and Collective Robotics

introduced. The central topic of the course stands in specific usage of the afore methods capable of execution with groups of robots and taking the advantage of their cooperation and coordination in groups. Labs and seminars are organized in a form of an Open Laboratory whereas the students will implement some fundamental algorithms and study their properties on real data.

B3M33PIS Industrial Information Systems Z,ZK 6

The aim of this course is to provide students with the necessary set of skills essential for the design and management of modern production systems. In the first part of the course, the students will learn about methods of modeling and simulation of discrete production systems. Students will then gain insight into methods for data analysis to optimize the production as well as into methods for process mining. The final part of the course deals with methods of data and knowledge modeling, which are necessary for explicit capture and machine utilization of information and knowledge about production.

B3M33PRO Advanced robotics Z,ZK 6

We will explain and demonstrate techniques for modelling, analyzing and identifying robot kinematics. We will explain more advanced principles of the representation of motion in space and the robot descriptions suitable for identification of kinematic parameters from measured data. We will explain how to solve the inverse kinematic task of 6DOF serial manipulators and how it can be used to identify its kinematic parameters. Theory will be demonstrated on simulated tasks and verified on a real industrial robot.

B3M33UI Artificial Intelligence Z,ZK 6

The course deepens and enriches knowledge of Al gained in the bachelor course Cybernetics and Artificial Intelligence. Students will get an overview of other methods used in Al, and will get a hands-on experience with some of them. They will master other required abilities to build intelligent agents. By applying new models, they will reiterate the basic principles of machine learning, techniques to evaluate models, and methods for overfitting prevention. They will learn about planning and scheduling tasks, and about methods used to solve them. Student will also get ackquainted with the basics of probabilistic graphical models, Bayesian networks and Markov models, and will learn their applications. Part of the course will introduce students to the area of again populat neural networks, with an emphasis to new methods for deep learning.

B3M35DRS Dynamics and Control Networks

Z,ZK | 6

This course responds to an ever-increasing demand for understanding contemporary networks large-scale complex systems composed of many components and subsystems interconnected into a single distributed entity. Herein, we will consider fundamental similarities between diverse areas such as e.g. forecasting the spread of global pandemics, public opinion dynamics and manipulation of communities through social media, formation controls for unmanned vehicles, energy generation and distribution in power grids, etc. Understanding such compelling issues goes far beyond the boundaries of any single physical, technological or scientific domain. Therefore, we will analyze phenomena across different domains, involving societal, economic and biological networks. For such networked systems, the resulting behavior depends not only on the characteristics of their individual components and details of their physical or logical interactions, but also on a precise way those components are interconnected the detailed interconnection topology. For that reason, the first part of the course introduces fundamental theoretical and abstract computational network analysis concepts; in particular, the algebraic graph theory, network measures and metrics and fundamental network algorithms. The second part of the course subsequently views networks as dynamical systems, studies their properties and ways in which these are controlled, using mainly methods of automatic control theory.

B3M35NES Nonlinear Systems and Chaos Z,ZK 6

The goal of this course is to introduce basics of the modern approaches to the theory and applications of nonlinear control. Fundamental difference when dealing with nonlinear systems control compared with linear case is that the state space approach prevails. Indeed, the frequency response approach is almost useless in nonlinear control. State space models are based mainly on ordinary differential equations, therefore, an introduction to solving these equations is part of the course. More importantly, the qualitative methods for ordinary differential equations will be presented, among them Lyapunov stability theory is crucial. More specifically, the focus will be on Lyapunov function method enabling to analyse stability of nonlinear systems, not only that of linear ones. Furthemore, stabilization desing methods will be studied in detail, among them the so-called control Lyapunov function concept and related backstepping method. Special stress will be, nevertheless, given by this course to introduce and study methods how to transform complex nonlinear models to simpler forms where more standard linear methods would be applicable. Such an approach is usually refered to as the so-called exact nonlinearity compensation. Contrary to the well-known approximate linearization this method does not ignore nonlinearities but compensates them up to the best possible extent. The course introduces some interesting case studies as well, e.g. the planar vertical take off and landing plane ("planar VTOL"), or a simple 2-dimensional model of the walking robot.

B3M35OFD Estimation, filtering and detection Z,ZK 6

This course will cover description of the uncertainty of hidden variables (parameters and state of a dynamic system) using the probability language and methods for their estimation. Based on bayesian problem formulation principles of rational behavior under uncertainty will be analyzed and used to develop algorithms for parameter estimations (ARX models, Gaussian process regression), filtering (Kalman filter) and detection (likelihood ratio theory). We will demonstrate numerically robust implementation of the algorithms applicable in real life problems for the areas of industrial process control, robotics and avionics.

B3M35ORROptimal and Robust ControlZ,ZK6B3M35PSRReal -Time Systems ProgrammingZ,ZK6

The goal of this course is to provide students with basic knowledge about software development for real-time systems, for example in control and embedded applications. The focus is on embedded systems equipped with a real-time operating system (RTOS). Lectures will cover real-time systems theory, which can be used to formally verify timing correctness of such systems. Another set of lectures will introduce methods and techniques used for development of safety-critical systems, whose failure may have catastrophic consequences. During labs, students will first solve a few simple tasks to familiarize themselves with basic components of VxWorks RTOS and to benchmark the used OS and hardware (Xilinx Zynq). The obtained metrics represent the typical criteria for assessing the suitability of a given platform for the given application. After the simple tasks, students will solve a complex task of time-critical motion control application which will require full utilization of RTOS features. All the tasks at the labs will be implemented in C (or C++) language.

B3M35SRL Flight Control Systems Z,ZK 6

The course is devoted to classical and modern control design techniques for autopilots and flight control systems. Particular levels are discussed, starting with the dampers attitude angle stabilizers, to guidance and navigation systems. Next to the design itself, important aspects of aircraft modelling, both as a rigid body and considering flexibility of the structure, are discussed.

B3M37KIN | Space Engineering Z,ZK 6

The subject acquaints students with the basics of physics of the space environment and the technologies used in space systems, satellites, spacecrafts and launchers and methods used for the design and preparation of space missions. Subject matter includes a detailed description of the instrumentation of satellites and spacecrafts and its resistance to external influences of the space environment, and analysis of instruments and systems for spacecrafts and methods of their testing. It provides a basic overview of the trajectories of spacecrafts and their applications. The course also covers optoelectronics in space systems, sensors used, their modeling and description. It discusses the principles of underlying calculations, simulations and their processing.

B3M37LRS Aeronautical radio systems Z.ZK 6

The course introduces students to the aeronautical radio engineering, aeronautical analogue, digital and satellite communication systems, aeronautical radio navigation including satellites navigation, primary secondary and passive radiolocation. The course gets students theoretical and practical knowledge of the operation of the aeronautical radio systems and their integration to the aircraft systems.

B3M38DITDiagnostics and TestingZ,ZK7B3M38INAIntegrated AvionicsZ,ZK6

The course Integrated Modular Avionics (IMA) focuses on a modern concept of the approach to the development and design of aircraft electronics (avionics), where the transition from distributed HW systems to SW blocks. They use high-speed connections to exchange data in applications related to paid air transport. The existing regulatory basis and airspace sharing define the requirements for the accuracy, reliability, and functionality of electronic systems even in the event of a failure. In the course, students will learn details about the requirements for so-called safety-critical multi-sensor systems, methods of data processing from predetermined systems, fault detection methods, selection of primary computer and control system in parallel architectures, bus technology, and methods of testing/certification of aircraft instruments.

B3M38MSE	Modern Sensors	Z,ZK	6
	An overview of sensors of physical quantities used in industry and in research and methods of signal processing.	•	
B3M38PSL	Aircraft Avionics	Z,ZK	6
The subject is focused into a field of aircraft avionics including principles, sensors, measurement and evaluation systems and signal/data processing methods. The subject goes into			
	systems, i.e. engine and aircraft monitoring systems, power systems, pressure-based systems, low-frequency navigation means, and	•	
introduces currentl	y used technology and methodology on aircraft and thus serves to understand fundamentals of avionics. Inertial navigation systems		nore details
50110000	as well as their aiding systems and sensors. The course focuses on both small and large aircraft as well as on UAV suited avio		
B3M38SPD	Data Acquisition and Transfer	Z,ZK	6
The aim of the course is to acquaint students with principles and limits of data transmission from sensors and similar sources of information for IoT and M2M, wireless sensor networks			
and specific algor	ithms, respecting the limiting conditions of their function. The basic algorithms of distributed information processing in sensor networ energy harvesting for powering the wireless nodes of the network, will be studied.	ks, as well as tecr	inology for
DOMOOV/DM	5. 5 1 5	7 71/	6
B3M38VBM	Videometry and Contactless Measurement on CCD and CMOS video sensors, and optoelectronic sensors in general and their use in contactless videometric measurement sys	Z,ZK	6
	or and its use for acquiring object parameters, optical projection system, design of measurement cameras and processing of their sign		
its leatures, beliavio	will design, realize and debug an independent project - 'Optoelectronic reflective sensor', during labs.	iai wiii be present	eu. Oludenia
B3M38VIN	Virtual Instrumentation	Z,ZK	6
B3M38ZDS	Analog Signal Processing and Digitalization	Z,ZK	6
B3MPROJ8	Project	Z	8
B3MPVT	·	KZ	6
Teamwork is the basis of most of the activities that people perform in companies and their personal lives. In this course, students can try how to solve a technical task in a team, how			
to cooperate, how to communicate together and how to solve problems such as project delays, how to include external influences in the plan, etc.			
BDIP30	Diploma Thesis	Z	30
	comprehensive work for the Master's degree study programme. A student will choose a topic from a range of topics related to his or h		
	y branch department or branch departments. The diploma thesis will be defended in front of the board of examiners for the compreh	ensive final exami	nation.
TV-V1	Physical education	Z	1
TVKLV	Physical Education Course	Z	0
TVKZV	Physical Education Course	Z	0
TVV	Physical education	Z	0
TVV0	Physical education	Z	0

For updated information see http://bilakniha.cvut.cz/en/f3.html Generated: day 2025-11-09, time 19:01.