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# MASTER OF SCIENCE, TECHNOLOGY AND HEALTH

2023-2024

YEAR 1

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## CONTROL AND ROBOTICS

### CONTROL SYSTEMS

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PROGRAMME SUPERVISOR(S):

Elwan HERY



# YEAR 1 - Autumn Semester

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## CORE COURSES

Course code	Title	ECTS Credits
ARTIN	Artificial Intelligence	6
CLACO	Classical Linear Control	5
MANIP	Modelling of Manipulators	4
MATOSS	Mathematical tools for signals and systems	4
MICRO	Embedded Computing	4
SIPRO	Signal Processing	5

## LANGUAGE COURSES

Course code	Title	ECTS Credits
CCE1	Cultural and Communication English	2
ESP1	Spanish Language	2
FLE1	French Language	2

# YEAR 1 - Spring Semester

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## CORE COURSES

Course code	Title	ECTS Credits
DYBAC	Dynamic Model Based Control	4
MOBRO	Mobile Robots	5
NOLCO	Non Linear Control Theory	4
OPTEC	Optimization Techniques	5
PROJECT	Group Project	6
SISIF	Systems Identification and Signal Filtering	4

## LANGUAGE COURSES

Course code	Title	ECTS Credits
CCE2	Cultural and Communication English	2
ESP2	Spanish Language	2
FLE2	French Language	2

# Master Programme - Control and Robotics - Control Systems

YEAR 1 - Autumn Semester

## Artificial Intelligence [ARTIN]

*LEAD PROFESSOR(S): Diana MATEUS LAMUS*

### Objectives

This course introduces the key notions of artificial intelligence and machine learning, essential today in dealing with the ubiquitous collection of increasing amounts of data. Starting from general theoretical concepts, we will review the most influential methods for unsupervised and supervised learning. The sessions will alternate between lectures and practical exercises in Python. Although the techniques will be presented from a broad and general perspective, the applications will focus on image and signal processing

### Course contents

- General concepts of machine learning
- Unsupervised methods for clustering
- From linear classification to Support Vector Machines (SVM)
- Decision trees and ensemble methods
- Neural networks and introduction to deep learning
- Evaluation measurements

### Course material

- [1] Bishop C. : Pattern Recognition and Machine Learning. Springer, 2006.  
 [2] Kevin Patrick Murphy. Probabilistic Machine Learning: An Introduction. 2022

### Assessment

Individual assessment: EVI 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	6	16 hrs	2 hrs	12 hrs	0 hrs	2 hrs

# Master Programme - Control and Robotics - Control Systems

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## Classical Linear Control [CLACO]

*LEAD PROFESSOR(S): Guy LEBRET*

### Objectives

Review the fundamentals of classical control for linear systems and provide a control methodology starting from the open loop analysis of the system to be controlled to the synthesis of a closed loop using classical PID type controllers (one degree of freedom controllers) which can be combined with a feedforward part (two degrees of freedom controllers).

### Course contents

- Description of SISO linear systems through the transfer function
- Analysis of behaviour (poles/zeros, first/second/more general systems, time domain/frequency domain responses etc)
- Definition the Control objectives (stability/performance, tracking/regulation)
- Nominal/robust stability (Routh, Nyquist criteria, stability margins).
- Nominal/robust performance and the unavoidable trades off between stability and performance.
- Synthesis of PID type controllers, using frequency approach tunings, in a classical closed loop (one degree of freedom controller strategy).
- Possibility of introducing a feedforward contribution which tries to "invert" the first closed loop obtained (two degrees of freedom controllers).

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

- Analysis of the dynamic behaviour of a SISO linear system
- Design a PID type controller as an example of a feedback controller
- Design a feedforward controller to increase tracking performance

### Course material

Recommended texts: course notes will be provided by the lecturer.

Further reading:

- "Modern Control Systems", R.C. Dorf and R.H. Bishop, Prentice Hall, 2011.
- "Control Systems Engineering", N. S. Nise, John Wiley & Sons, 2011.
- "Control system design", G.C. Goodwin, S.F. Graebe and M.E. Salgado, Prentice Hall, 2001.
- "Multivariable Feedback Control Analysis and Design", D.S. Skogestad and I. Postlethwaite, Wiley, 2005.

### Assessment

Individual assessment: EVI 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	5	22 hrs	4 hrs	4 hrs	0 hrs	2 hrs

# Master Programme - Control and Robotics - Control Systems

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## Modelling of Manipulators [MANIP]

LEAD PROFESSOR(S): Olivier KERMORGANT

### Objectives

This course introduces the modelling and basic control of serial robot arms. The topics include robot architecture and modeling conventions, forward and inverse kinematic model, differential kinematic modelling and the basics of trajectory planning and tracking.

At the end of the course, students will be able to:

- Have a clear view of 3D geometry, including rotation parametrization and velocity screws
- Define a table of modified Denavit-Hartenberg parameters to model a robot from a sketch
- Compute (manually or with software) the direct and differential kinematic models
- Derive the inverse kinematic model for standard manipulators (6R / 3P3R)
- Understand position and velocity control modes
- Know how to generate a trajectory from a sequence of 3D waypoints
- Know various symbolic or numeric software tools that can be used to model and control robots

### Course contents

- Robot architecture, joint and operational spaces
- Homogeneous transformation matrices, 3D geometry, velocity screw
- Modified Denavit-Hartenberg parametrization and direct kinematics
- Definition and computation of the robot Jacobian
- Inverse kinematics in exact and iterative forms
- Trajectory generation
- Basic position and velocity control modes (trajectory / velocity tracking)

Exercises will involve modelling and simulating various serial manipulators.

### Course material

- Slides and labs are available online.
- W. Khalil, and E. Dombre, Modeling, identification and control of robots, Hermes Penton, 2002.

Further reading:

- 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.

### Assessment

Individual assessment: EVI 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	4	16 hrs	0 hrs	14 hrs	0 hrs	2 hrs

## Mathematical tools for signals and systems [MATOSS]

LEAD PROFESSOR(S): Sébastien BOURGUIGNON

### Objectives

This course provides basic mathematical knowledge required for understanding theory and developing relevant methods for the analysis of signals and systems.

One part is dedicated to probability and statistics. It addresses the characterization and the processing of random signals by means of statistical tools. It thus provides the theoretical foundations used in the development of signal modelling methods for the resolution of numerous problems: biomedical signal and image processing (diagnosis, tools to assist the disabled), music signal processing (restoration of old recordings, reconstruction of the score, coding and compression), positioning systems (fusion of GPS and odometry), etc. Another part is dedicated to understanding and modeling linear operators by means of matrix representations, and exploit the corresponding formalism with standard linear algebra tools such as matrix rank, determinant, matrix inversion, vector spaces, particular matrix properties and, most of all, eigenvalue problems. Such tools are widely used for establishing and understanding state-space representations in control, solving multivariate differential equations, manipulating linear transforms such as the Discrete Fourier Transform or wavelet transforms.

At the end of the course, the students will be able to:

- Provide a statistical description of a random process
- Solve a statistical estimation problem in a practical situation
- Develop a numerical algorithm to calculate and to characterize the solution
- Characterize solutions to linear systems
- Formulate a linear operation applied on vectors by means of a matrix and study its main properties
- Solve eigenvalue problems, exploit diagonalization and reduce quadratic forms

### Course contents

#### Probability and statistics

- Probability theory: random vectors, density, mean, variance.
- Time analysis, frequency analysis: random signals, autocorrelation, power spectral density.
- Classical estimation Theory, Bayesian estimation: maximum likelihood (ML) estimation, minimum mean square error (MMSE) estimator, maximum a posteriori (MAP) estimator, linear minimum mean square error (LMMSE).
- Markov chains, Markov processes
- Statistical filtering: Kalman

#### Linear algebra

- Vectors and matrices, basic operations
- Solutions to Linear systems: existence, uniqueness, resolution; linear independence and matrix rank
- Determinants. Matrix inversion
- Inner product spaces, linear transformations
- Matrix eigenvalue problems, eigenbases and diagonalization
- Quadratic forms, transformation into principal axes

### Course material

- [1] Probability, Random Variables and Stochastic Processes. A. Papoulis, S.U. Pillai. Mcgraw Hill.
- [2] Fundamentals of Statistical Signal Processing, Vol.1: Estimation theory, S. Kay, Prentice Hall.
- [3] Advanced Engineering Mathematics, E. Kreiszig, 10th edition (posthumous), 2011, Wiley.

## Assessment

Individual assessment: EVI 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	4	16 hrs	10 hrs	4 hrs	0 hrs	2 hrs

# Master Programme - Control and Robotics - Control Systems

YEAR 1 - Autumn Semester

## Embedded Computing [MICRO]

*LEAD PROFESSOR(S): Mickael HILAIRET*

### Objectives

At the end of the course the students will be able to:

- understand the architecture of a microcontroller;
- design a low-level driver to access a peripheral of a microcontroller and deal with microcontroller interrupts;
- design a bare metal application, i.e. without any real time operating system.

### Course contents

The first part of the course deals with the software environment for deeply embedded systems:

- data representation
- cross compiler: bit operations, memory model, common C design rules, low level C and assembly specific attributes
- debugging : breakpoints, memory watch, etc

The second part introduces some basic hardware peripherals of a microcontroller to interact with the environment:

- standard GPIO
- timers and PWM
- interrupts, external interrupts
- serial communication peripherals

The third part of the module focuses on the design of both bare metal applications and driver, including concurrent execution of both software and hardware parts.

### Course material

- Philip Koopman, Better Embedded Software Systems, Drumndrochit Education LLC, 2010
- D. Patterson & J. Hennessy, Computer Organization and Design – ARM Edition, Morgan Kaufmann, 2017

### Assessment

Individual assessment: EVI 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	4	12 hrs	2 hrs	16 hrs	0 hrs	2 hrs

# Master Programme - Control and Robotics - Control Systems

YEAR 1 - Autumn Semester

## Signal Processing [SIPRO]

LEAD PROFESSOR(S): *Eric LE CARPENTIER*

### Objectives

- To interpret the spectral representations of signals
- To understand the time sampling of signals (sample rate, anti-aliasing filter etc.)
- To model a system using the transfer functions language
- To model a system using the state space language
- To switch from one representation to the other
- To link the physical phenomena to the parameters of these representations (stability, response velocity etc.)
- To simulate these mathematical representations with adapted scientific software tools (Matlab, Simulink)

### Course contents

- Analysis of continuous-time and discrete-time signals
  - o Fourier, Laplace and z transforms
  - o Sample, hold, quantization, Shannon theorem
- Modelling of continuous-time and discrete-time linear time invariant (LTI) systems
  - o Transfer function, state space representation
  - o Poles, zeros, stability
  - o Time response, frequency response
  - o Sampling
  - o Simulation (Matlab Simulink)
  - o First-order and second-order systems
- Design of an actual digital control implementation
  - o Analog to Digital Converter, Digital to Analog converter
  - o Sample and hold
  - o Link with the previous mathematical representations
- Lab work
  - o A simple encoder
  - o Spacecraft control simulation

### Course material

- Modern Signals and Systems, H. Kwakernaak, R. Sivan, Prentice Hall.
- Signals and Systems, R. Baraniuk, <http://www.eng.ucy.ac.cy/cpitris/courses/ece623/notes/SignalsAndSystems.pdf>
- Signal processing. Introduction to signals and systems theory, E. Le Carpentier, <https://hippocampus.ec-nantes.fr/mod/resource/view.php?id=9179>

### Assessment

Individual assessment: EVI 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	5	16 hrs	0 hrs	14 hrs	0 hrs	2 hrs

## Cultural and Communication English [CCE1]

LEAD PROFESSOR(S): David TROYA

### Objectives

This course aims at improving your critical thinking and persuasion skills in English. Using documentaries, we will explore, discuss and debate a range of cultural, political, social, and environmental issues relevant to current world events.

Speaking and understanding English as a second or third language is a great achievement, but does it mean you are an effective communicator? The next step involves, among other things, critical thinking and persuasive skills, both of crucial importance in the modern professional environment. We will address these issues by analyzing documentaries that will lead to formal debates.

Several competencies will be developed through class exercises. Oral presentations will be an opportunity put your verbal as well as your non-verbal communication skills into practice. During debate, you will be able to sharpen your analytical skills, provide constructive feedback, defend an argument, and prove a point.

#### Course objectives

- Improving your communication skills
- Becoming an active listener
- Enhancing your non-verbal communication skills
- Developing critical thinking toward media
- Boosting leadership skills through moderating
- Organizing evidence and arguments

### Course contents

Each session will be dedicated to a particular cultural, political, social or environmental topic of relevance in the wider anglophone world. Each topic will include multimedia material in the form of a short documentary or documentary excerpt. During class, students will lead a primer presentation, a moderated discussion and a formal debate.

#### Primer Presentation:

In pairs, you will hold a short talk to prime us on the topic of that week's documentary: you will introduce us to the topic by setting it in a wider context and establishing what's at stake.

#### Moderated Discussion :

In pairs, you will moderate a discussion related to the themes explored by the documentary. Moderators will come prepared with open-ended questions pertaining to the strengths and weakness of the documentary. They will distinguish between content and form and encourage critical, constructive opinions.

#### Formal Debate:

What's the difference between an opinion and an argument? You will soon find out. After the moderated discussion, we will brainstorm potential topics for debate, and follow the British Parliamentary model to sharpen your research, critical thinking,

and persuasive skills.

During the debate, each speaker will be assigned an audience member who evaluates their individual performance and provides a short debrief. A panel of two judges will determine which side wins.

## Course material

Written and televised press, information and digital tools, general documents, business environment and company strategies. Internet conferences (Ted Talks, etc.), our own educational materials on Hippocampus (Moodle).

## Assessment

Individual assessment: EVI 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	2	0 hrs	32 hrs	0 hrs	0 hrs	0 hrs

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YEAR 1 - Autumn Semester

## Spanish Language [ESP1]

LEAD PROFESSOR(S): Marta HERRERA

### Objectives

For beginners:

- Practice and reinforcement of the five skills (oral and written expression and comprehension as well as interaction)
- Acquisition of vocabulary and linguistic structures
- Be able to talk about yourself and those around you
- Be able to express oneself during daily activities
- Know how to give your opinion

For advanced students:

- Practice and reinforcement of the five skills (oral and written expression and comprehension as well as interaction)
- Acquisition of specialised vocabulary
- Be able to understand the essential content of concrete or abstract subjects including a technical discussion
- Be able to communicate spontaneously and fluently
- Be able to express oneself in a clear and detailed manner, to express an opinion on a topical subject

### Course contents

For beginners:

- Personal environment (introduce yourself, express yourself, your tastes, your character, your hobbies, etc.), your surroundings (friends, family, location, climate), your interests (sports, leisure)
- Present tense (regular and irregular)
- Language patterns to express habit, obligation, "gustar" and its equivalents,
- Possessive adjectives
- Differences between "es", "está", "hay"
- Use of "por" and "para"
- Adverbs and frequency patterns
- Numeral adjectives

For advanced students:

- Knowledge of the Hispanic world (economic, technical, cultural and social environment)
- Present tense (regular and irregular)
- Imperative
- Past tenses
- Direct / indirect style
- Future tense
- Conditional tense
- Present and past subjunctive moods

### Course material

Preparation manuals, our own tailor-made documents, written and internet press, general civilization documents, digital tools

### Assessment

Individual assessment: EVI 1 (coefficient 1)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
Spanish	2	0 hrs	32 hrs	0 hrs	0 hrs	0 hrs

# Master Programme - Control and Robotics - Control Systems

YEAR 1 - Autumn Semester

## French Language [FLE1]

LEAD PROFESSOR(S): *Silvia ERTL*

### Objectives

The objective is to familiarize the learner with the French language and French culture through an entertaining task-based communicative language teaching, focused on speaking combined with:

- Phonetics
- Self-correcting exercises on our learning platform
- Learning Lab activities
- Project work
- Tutoring

Course objectives include the acquisition and reinforcement of vocabulary, syntax, and pronunciation by both traditional means and through the use of digital resources.

Students will learn general French, develop language skills of oral and written comprehension and expression.

After completing this course (32 hours + personal work), the students will be able to communicate in spoken and written French, in a simple, but clear manner, on familiar topics in the context of study, hobbies etc. Another important goal of this course is to introduce the student to French culture. At the end of the course (2 semesters), complete beginners can achieve an A1 level and some aspects of the A2 of The Common European Framework of Reference for Languages. More advanced students may aim for B1/B2 levels.

### Course contents

Full range of practical communication language exercises: reading comprehension, listening comprehension, written expression, oral expression.

Learners will be able to use the foreign language in a simple way for the following purposes:

1. Giving and obtaining factual information:

- personal information (e.g. name, address, place of origin, date of birth, education, occupation)
- non-personal information (e.g. about places and how to get there, time of day, various facilities and services, rules and regulations, opening hours, where and what to eat, etc.)

2. Establishing and maintaining social and professional contacts, particularly:

- meeting people and making acquaintances
- extending invitations and reacting to being invited
- proposing/arranging a course of action
- exchanging information, views, feelings, wishes, concerning matters of common interest, particularly those relating to personal life and circumstances, living conditions and environment, educational/occupational activities and interests, leisure activities and social life

3. Carrying out certain transactions:

- making arrangements (planning, tickets, reservations, etc.) for travel, accommodation, appointments, leisure activities
- making purchases
- ordering food and drink

### Course material

Preparation manuals, our own tailor-made documents, written and televised press, internet, general civilization documents, digital tools, our own educational materials on Hippocampus (Moodle).

## Assessment

Individual assessment: EVI 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	2	0 hrs	48 hrs	0 hrs	0 hrs	0 hrs

# Master Programme - Control and Robotics - Control Systems

YEAR 1 - Spring Semester

## Dynamic Model Based Control [DYBAC]

LEAD PROFESSOR(S): Guy LEBRET / Sébastien BRIOT

### Objectives

To show that using in a control law "a dynamic model" of a dynamical system can be the base of a fruitful control methodology. This course is an extension of two courses: Classical Linear Control and Modelling of Manipulators. In the first part (16h), for linear multivariable systems, the model is used, first of all, to obtain observer-based controllers (state space approach of linear multivariable systems) as the feedback part of the control law, and secondly, in a possible feedforward part.

In the second part (16h), it is shown how the dynamic model of mechanisms or, more specifically, serial robots can be obtained, as this model is the basis of the so-called "computed torque control law". Different formalisms for the computation of the dynamic model will be explored (Newton-Euler, Lagrange equations).

Clearly, the objective of the course is to present a unified methodology to obtain control laws. In this methodology, once the dynamic model has been obtained, then the non-linear coupled MIMO systems can be linearized and decoupled, and finally the linear methodology of the first part can be applied.

### Course contents

Part 1 state space approach of linear multivariable systems:

- Time domain state response, modal decomposition of the response
- Controllability, observability
- Observer-based controllers
- Possible two degrees of freedom controllers.

Part 2, mechanisms or more specifically, serial robots:

- Recalls of classical mechanics
- Newton-Euler equations
- Euler-Lagrange equations
- Optimal computation of dynamic models for serial robots (recursive formalisms)

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

- Use all classical tools of the linear state space approach to analyse (mode, controllability, etc) and design observer-based controllers.
- Compute the dynamic model of open-loop mechanisms and robots
- Evaluate the benefit of the use of a dynamical model in a control law.

### Course material

Recommended texts: Course notes will be provided by the lecturers.

Further reading:

- "Control system design", G.C. Goodwin, S.F. Graebe and M.E. Salgado, Prentice Hall, 2001.
- "Linear Multivariable Control, A Geometric Approach", W.M.Wonham. Springer Verlag, New York, 1985.
- "Linear Systems", T. Kailath, Prentice-Hall, New Jersey, 1980.
- "Modelling, Identification and Control of Robots" W. Khalil and E. Dombre, Hermes Penton, Ltd, 2002

### Assessment

Individual assessment: EVI 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	4	22 hrs	4 hrs	4 hrs	0 hrs	2 hrs

# Master Programme - Control and Robotics - Control Systems

YEAR 1 - Spring Semester

## Mobile Robots [MOBRO]

LEAD PROFESSOR(S): Gaëtan GARCIA

### Objectives

The objective of the course is to provide students with the necessary tools to model, localize and control conventional wheeled mobile robots, along with tools to plan their path.

### Course contents

The following subjects will be addressed:

- Modelling of wheeled Robots: Constraint equations, Classification of robots using degrees of mobility and steerability, Posture kinematic model, Configuration kinematic model, Motorisation of wheels.
- Localization: Relative localization using odometry, Absolute localisation, Localization sensors, Localization using extended Kalman filtering. Observability analysis of localization problems.
- trajectories planing : maps et navigable space, global and local trajectories planing.
- Control: Controllability and stabilization, static and dynamic feedback linearization, non-linear control based on Lyapunov functions.

Practical Work:

- The students implement a Kalman filter-based localization algorithm using data recorded with a real robot.
- Trajectories tracking with various control laws.

### Course material

- "Theory of robot control", Carlos Canudas de Wit, Bruno Siciliano, Georges Bastin, Springer Science & Business Media, 2012 - 392 pages.
- "Wheeled Mobile Robots—Kinematic Modelling", G. Garcia, Class material in book form.
- "Mobile robots—Localization", G. Garcia, Class material in book form.
- "Principles of robot motion", H. Choset et. al., Bradford books, MIT Pres.

### Assessment

Individual assessment: EVI 1 (coefficient 1)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	5	20 hrs	0 hrs	10 hrs	0 hrs	2 hrs

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## Non Linear Control Theory [NOLCO]

LEAD PROFESSOR(S): Franck PLESTAN

### Objectives

The goal is to provide the fundamentals of modern nonlinear control theory. Analysis and control of nonlinear systems are considered using a so-called algebraic approach. Many examples taken from different fields of applications demonstrate the feasibility of the methodologies. After completing this course, the students will be able to:

- Understand the theoretical fundamentals on the control of non-linear systems,
- Apply advanced nonlinear control to a variety of systems

### Course contents

- Introduction to the algebraic approach for nonlinear systems and its mathematical tools.
  - Structural analysis, concepts of relative degree, of controllability and accessibility.
- Introduction to stability - Lyapunov
- Control methods: feedback linearization, decoupling, reference trajectory tracking, sliding mode control, model-free control.
  - Practical Work: case studies on an inverted pendulum and a PVTOL model

### Course material

- G. Conte, et al., Algebraic Methods for Nonlinear Control Systems. Theory and Applications, Springer, 2006.
- Isidori, Nonlinear Control Systems. 2nd edition, Springer, 1989.
- Y. Shtessel et al., Sliding Mode Control and Observation, Birkhauser, 2014.
- H. Khalil, Nonlinear systems – 2nd edition, Prentice Hall, 1996.

### Assessment

Individual assessment: EVI 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	4	16 hrs	2 hrs	12 hrs	0 hrs	2 hrs

# Master Programme - Control and Robotics - Control Systems

YEAR 1 - Spring Semester

## Optimization Techniques [OPTTEC]

*LEAD PROFESSOR(S): Alexandre GOLDSZTEJN*

### Objectives

The course presents different theoretical and computational aspects of a wide range of optimization methods for solving a variety of problems in different fields related to the Master's program. The main objective of this course is to give the students the ability to formalise, select the appropriate method, implement the optimisation problem and then analyse the results in order to take the best decision regarding the objectives, variables and constraints. The students will be able to understand different theoretical and computational aspects of a wide range of optimization methods.

### Course contents

- Basic concepts of optimization
- Basic concepts of optimization
- Unconstrained optimization
  - First and second order optimality conditions
  - The steepest descent method
  - Advanced descent methods
- Constrained optimization
  - First and second order optimality conditions
  - Extension of unconstrained methods
  - Methods with penalization
- Use of optimization toolboxes

### Course material

Jorge Nocedal, Stephen J. Wright: Numerical Optimization, Springer New York, NY.  
Dimitri P. Bertsekas: Nonlinear Programming, Athena Scientific.

### Assessment

Individual assessment: EVI 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	5	14 hrs	0 hrs	16 hrs	0 hrs	2 hrs

# Master Programme - Control and Robotics - Control Systems

YEAR 1 - Spring Semester

## Group Project [PROJECT]

*LEAD PROFESSOR(S): Gaëtan GARCIA*

### Objectives

To contribute to solving a scientific, technological or theoretical problem proposed by any of the instructors of the master (professors, assistant professors, researchers etc.) or industrial partners.

### Course contents

The students (individually or often as a group of two) organize the project. Depending on the subject, a bibliography may be necessary, an original methodology or solution can be proposed or it can involve purely the application of techniques learned throughout the courses.

### Course material

To be provided by the supervisor(s) if necessary.

### Assessment

Collective assessment: EVC 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	6	0 hrs	0 hrs	0 hrs	32 hrs	0 hrs

# Master Programme - Control and Robotics - Control Systems

YEAR 1 - Spring Semester

## Systems Identification and Signal Filtering [SISIF]

LEAD PROFESSOR(S): Mira RIZKALLAH

### Objectives

Signal filtering is a basic operation in signal processing which allows, for instance, undesired content to be deleted. The first part of this course deals with methods to design analog and digital filters and their application for the processing of real signals. The second part of the course focuses on experimental modeling of time series. It provides a detailed description of the time series forecasting and modeling chain from data acquisition to model validation.

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

- specify all the desired properties of a linear filter
- design a linear filter fulfilling the specifications and apply it to a real signal
- model time series and estimate model parameters
- undertake times series forecasting, estimate future values of a time series.

### Course contents

#### 1. Signal filtering

- principles of linear filtering, filter characterization in the frequency domain
- analog filter synthesis
- digital filter synthesis (FIR, IIR)

#### 2. Time series analysis

- Time series basics: important features on a time series plot, Auto-regressive(AR) model, Autocorrelation function (ACF)
- Moving Average (MA) models, partial autocorrelation, useful notations (backshift operators etc)
- Identifying and estimating ARMA, ARIMA models; using ARIMA models to forecast future values.

#### 3. Applications

- Audio signal filtering
- Time series 1: fMRI BOLD signals, time series analysis, plotting, correlation, ACF, PACF, stationarity ..
- Time series 2: Forecasting the climate change in a specific city in the worm (temperature forecasting) (based on past values and models)

### Course material

H. Kwakernaak and R. Sivan, Modern signals and systems, Prentice Hall, Englewood Cliffs, 1991

C. Chatfield and H. Xing, The Analysis of Time Series: An Introduction with R, 2019

### Assessment

Individual assessment: EVI 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	4	12 hrs	10 hrs	8 hrs	0 hrs	2 hrs

# Master Programme - Control and Robotics - Control Systems

YEAR 1 - Spring Semester

## Cultural and Communication English [CCE2]

*LEAD PROFESSOR(S): David TROYA*

### Objectives

Interview techniques and communicational English:

- Understand the general concepts of interactive communication
- Build a media project
- Acquire interview techniques
- Understand the process of sourcing and checking facts and figures
- Understand issues related to plagiarism
- Create a bibliography
- Behavioral skills in an inter-cultural environment:
- Strengthen self-confidence and capacity for interaction
- Develop active listening and reformulation skills
- Develop networking skills

### Course contents

Cultural and Communicational English: exercises to explore in practice the areas of culture and communication.

Media project (for example: prepare, conduct and promote interviews for a radio programme: L'Heure Centralienne (<http://www.euradionantes.eu/emission/l-heure-centralienne>), with the contribution of professors, PhD students, industrial partners, industry players at fairs, etc.

### Course material

Written and televised press, information and digital tools, general documents business environment and company strategies. Internet conferences (Ted Talks, etc.), our own educational materials on Hippocampus (Moodle).

### Assessment

Individual assessment: EVI 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	2	0 hrs	32 hrs	0 hrs	0 hrs	0 hrs

# Master Programme - Control and Robotics - Control Systems

YEAR 1 - Spring Semester

## Spanish Language [ESP2]

LEAD PROFESSOR(S): Marta HERRERA

### Objectives

For beginners:

Practice and reinforcement of the five skills (oral and written expression and comprehension as well as interaction)

Acquisition of vocabulary and linguistic structures

Be able to talk about yourself and those around you

Be able to express oneself during daily activities

Know how to give your opinion

For advanced students:

Practice and reinforcement of the five skills (oral and written expression and comprehension as well as interaction)

Acquisition of specialised vocabulary

Be able to understand the essential content of concrete or abstract subjects including a technical discussion

Be able to communicate spontaneously and fluently

Be able to express oneself in a clear and detailed manner, to express an opinion on a topical subject

### Course contents

For beginners:

Personal environment (introduce yourself, express yourself, your tastes, your character, your hobbies, etc.), your surroundings (friends, family, location, climate), your interests (sports, leisure)

Present tense (regular and irregular)

Language patterns to express habit, obligation, "gustar" and its equivalents,

Possessive adjectives

Differences between "es", "está", "hay"

Use of "por" and "para"

Adverbs and frequency patterns

Numeral adjectives

For advanced students:

Knowledge of the Hispanic world (economic, technical, cultural and social environment)

Present tense (regular and irregular)

Imperative

Past tenses

Direct / indirect style

Future tense

Conditional tense

Present and past subjunctive moods

### Course material

Preparation manuals, our own tailor-made documents, written and internet press, general civilization documents, digital tools

### Assessment

Individual assessment: EVI 1 (coefficient 1)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
Spanish	2	0 hrs	32 hrs	0 hrs	0 hrs	0 hrs

# Master Programme - Control and Robotics - Control Systems

YEAR 1 - Spring Semester

## French Language [FLE2]

LEAD PROFESSOR(S): *Silvia ERTL*

### Objectives

The objective is to familiarize the learner with the French language and French culture through an entertaining task-based communicative language teaching, focused on speaking combined with:

- Phonetics
- Self-correcting exercises on our learning platform
- Learning Lab activities
- Project work
- Tutoring

Course objectives include the acquisition and reinforcement of vocabulary, syntax, and pronunciation by both traditional means and through the use of digital resources.

Students will learn general French, develop language skills of oral and written comprehension and expression.

After completing this course (32 hours + personal work), the students will be able to communicate in spoken and written French, in a simple, but clear manner, on familiar topics in the context of study, hobbies etc. Another important goal of this course is to introduce the student to French culture. At the end of the course (2 semesters), complete beginners can achieve an A1 level and some aspects of the A2 of The Common European Framework of Reference for Languages. More advanced students may aim for B1/B2 levels.

### Course contents

Full range of practical communication language exercises: reading comprehension, listening comprehension, written expression, oral expression.

Learners will be able to use the foreign language in a simple way for the following purposes:

1. Giving and obtaining factual information:

- personal information (e.g. name, address, place of origin, date of birth, education, occupation)
- non-personal information (e.g. about places and how to get there, time of day, various facilities and services, rules and regulations, opening hours, where and what to eat, etc.)

2. Establishing and maintaining social and professional contacts, particularly:

- meeting people and making acquaintances
- extending invitations and reacting to being invited
- proposing/arranging a course of action
- exchanging information, views, feelings, wishes, concerning matters of common interest, particularly those relating to personal life and circumstances, living conditions and environment, educational/occupational activities and interests, leisure activities and social life

3. Carrying out certain transactions:

- making arrangements (planning, tickets, reservations, etc.) for travel, accommodation, appointments, leisure activities
- making purchases
- ordering food and drink

## Course material

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Preparation manuals, our own tailor-made documents, written and televised press, internet, general civilization documents, digital tools, our own educational materials on Hippocampus (Moodle).

## Assessment

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Individual assessment: EVI 1 (coefficient 1.0)

LANGUAGE OF INSTRUCTION	ECTS CREDITS	LECTURES	TUTORIALS	LAB	PROJECT	EXAM
English	2	0 hrs	48 hrs	0 hrs	0 hrs	0 hrs