Syllabus Course description

Course title	Fundamentals of programming for control
Course code	46050
Scientific sector	Ing-inf 04
Degree	PhD programme Advanced System Engineering
	(1st year)
Semester	Ι
Year	Ι
Academic year	2020-2021
Credits	3
Modular	No

Total lecturing hours	30
Attendance	Attendance of lectures is strongly recommended but is
	not required
Prerequisites	None
Course page	

objectives p e c c N si lis d lo d lo m p lis lo d lo m p lis lo d lo m p lis lo m p lis lo m p lis lo m lo m <th>he course provides an introduction to python rogramming techniques applied to the basic rinciples of automatic control. Examples and xercises that use python to solve problems in ontrols and robotics will be given. More specifically, Python programming: strings and tring manipulation, comments, functions, tuples, sts, aliasing, dictionaries, testing, debugging, xceptions, assertions, creating python classes and ata types, for loops, while loops, 2D lists and pops, plotting graphs, input from files, modules, natrix operations, solving linear differential equations rogramatically, tuples, ntroduction to linear control theory: Systems, states, Dubin's car example, solution of uncontrolled and ontrolled systems, Basic PID control, peak and time elated criterea, ziegler-nichols tuning, stability: hase plots, Lypanov's method, perturbations, root pocus, using python for desinging a phase-lag ontroller, reference trajectories, path following PID, rajectory tracking, the soft landing problem, Optimal ontrol: time optimal, terminal control, linear regulator <i>v</i>ith quadratic costs, processing sensor information nrough python.</th>	he course provides an introduction to python rogramming techniques applied to the basic rinciples of automatic control. Examples and xercises that use python to solve problems in ontrols and robotics will be given. More specifically, Python programming: strings and tring manipulation, comments, functions, tuples, sts, aliasing, dictionaries, testing, debugging, xceptions, assertions, creating python classes and ata types, for loops, while loops, 2D lists and pops, plotting graphs, input from files, modules, natrix operations, solving linear differential equations rogramatically, tuples, ntroduction to linear control theory: Systems, states, Dubin's car example, solution of uncontrolled and ontrolled systems, Basic PID control, peak and time elated criterea, ziegler-nichols tuning, stability: hase plots, Lypanov's method, perturbations, root pocus, using python for desinging a phase-lag ontroller, reference trajectories, path following PID, rajectory tracking, the soft landing problem, Optimal ontrol: time optimal, terminal control, linear regulator <i>v</i> ith quadratic costs, processing sensor information nrough python.
Learning outcomes K	nowledge and understanding

Learning outcomes	Knowledge and understanding	
	1. Basic software design procedures	

 How to program in Python Basics of linear control: controllability, optimization, stability Basics of modelling and simulation <u>Applying knowledge and understanding</u> Writing programs for lab exercises during the lectures <u>Making judgements</u> Choosing the right data type and programming approaches <u>Communication skills</u> Writing lab reports will require presenting information and ideas in clear language <u>Learning skills</u>
Learning skills Basic foundatsions for further study in Engineering

Assessment	<u>Form</u>	<u>%</u>
	Exercise	40
	Final exam	60
Assessment language	English	
Evaluation criteria and	In-class exercises: completeness and correctness of	
criteria for awarding marks	answers, level of understanding Written final exam: Completeness and correctness of	
	answers	

Required readings	Notes will be provided on OLE	
Supplementary readings	Additinal books may be recommended during the course	