

ELLIIT Ph.D. Course:  
*Advanced Motion Planning and Control*  
—*Project Seminar*

Björn Olofsson

Division of Vehicular Systems  
Linköping University

May 28, 2021

# Agenda

<b>Time</b>	<b>Speaker</b>	<b>Title</b>
13:15–13:35	Anja Hellander	Task and Motion Planning for a Truck
13:35–13:55	Jonas Nordlöf	Obstacle Avoidance and Path Tracking Using Neural Networks on a Physical Autonomous Vehicle
13:55–14:15	Birgitta Wingqvist	Planning and Tracking Control for Marine Vessels
14:15–14:35	Theodor Westny	Combining Physics-based Models and Deep Learning for Vehicle Trajectory Prediction
14:35–14:45	<i>Break</i>	
14:45–15:05	Carl Hynén	Path-planning for Ships under Wind Uncertainty
15:05–15:25	Jian Zhou	Motion Planning in Dynamic Environments with Multiple Vehicles
15:25–15:45	Faseeh Ahmad	Cartesian Compliance Control and Trajectory Generation

# Written Project Report

- ▶ A short written report is to be submitted by June 4, 2021.
- ▶ Suggested report structure:
  - ▶ Background
  - ▶ Problem Definition
  - ▶ Methods and Implementation
  - ▶ Results
  - ▶ Discussion and Conclusions
- ▶ Report can be written as a conference paper draft.
- ▶ Please also submit a pdf file with the presentation slides along with the report.