

AMR 2020/21: Final Project Group Assignments

(supervisor name in parentheses)

FP2. Quadruped gait generation using IS-MPC (Filippo Smaldone)

Salustri, Scotti, Sabatucci

FP3. Discrete-time Control Barrier Functions for safe vehicle control (Tommaso Belvedere)

Bonuomo, Pennese, Vulcano

FP4. Optimal trajectory generation in the Duckietown environment (Tommaso Belvedere)

Giacomini, Pepe, Rossetti

FP5. Safe kinematic control for humanoid robots using CBFs (Paolo Ferrari)

Bellan, Caciolai, De Rebotti

FP6. Enhancing kinodynamic RRT using CBF-based steering (Paolo Ferrari)

Giunta, Nicotra, Paggetti

FP7. Improving footstep planning algorithms by efficient nearest neighbor searching (Michele Cipriano)

Motoi, Saraceni, Sensolini Arrà

FP9. Strategies for robust gait generation in humanoid robots (Nicola Scianca)

Pustina, Rabbiolo, Santosuosso

FP10. Learning-based NMPC for autonomous race cars (Giulio Turrisi)

Cardia, Ragno, Savoia

FP11. 3D information-based collision avoidance for safe mobile robot navigation (Valerio Modugno)

Caprari, Castro, Fioretti

FP12. Safe robust control by blending RL policies with stochastic MPC (Valerio Modugno)

Fonseca Aponte, Giannone, Sebeto