

Modelling, identification and motion estimation of unmanned marine vehicles

Massimo Caccia

Consiglio Nazionale delle Ricerche
Istituto di Studi sui Sistemi Intelligenti per l'Automazione
Via Amendola 122 D/O, 70126, Bari, Italy
massimo.caccia@ge.issia.cnr.it

Why this tutorial?

- Assumptions
 - Models are perfect representations of the systems
 - Measurements are ideal or, in the worst case, noise is Gaussian
 - Control force is known
- Reality
 - Models are approximated representations of the systems
 - Measurement noise is not Gaussian
 - Control force could not be known
- nevertheless...

- what we study is fundamental to manage reality, i.e. to **control the robot motion...**

How?

- I'm going to share with you my practical experience

