UNIVERSITÀ DI TRENTO
Dipartimento di Ingegneria Industriale

13-21 MAY 2026

MOTION CONTROL OF AUTONOMOUS ROBOTIC VEHICLES

This course addresses the modeling, analysis, and control of autonomous robotic vehicles using modern nonlinear control theory. It covers both fundamental and advanced topics, with emphasis on Lyapunov-based analysis, robust and safety-critical control design, cooperative motion control, and practical implementation aspects. Theoretical concepts are systematically illustrated through examples drawn from ground robots, marine vehicles, and unmanned aerial vehicles (UAVs).

13 May 2026, 13:30-16:30, Seminar Room

15 May 2026, 14:00-17:00, Seminar Room

19 May 2026, 14:00-17:00, Seminar Room

21 May 2026, 14:00-17:00, Seminar Room

Speaker: António Pedro Aguiar

Full Professor, Department of Electrical and Computer Engineering
Faculty of Engineering
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PHD COURSE

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