Bachelor's Thesis

Duckietown - Lane Following with Platooning

At LIS, we want to use the Duckietown hardware and software ecosystem to experiment with our reinforcement learning-based learning classifier tables (LCT) as part of the control system of the Duckiebots: https://www.ce.cit.tum.de/lis/forschung/aktuelle-projekte/duckietown-lab/.

More information on Duckietown can be found at https://www.duckietown.org/.

In this student work, we want to extend the bot's current abilities (lane following).

The goal of this work is to enable the bots to follow each other with a constant distance. At the end, there should be a seamless integration in the Lane Following Pipeline.

Prerequisites

- Knowledge about Image Processing
- Python

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