MULTI-SENSOR DATA FUSION										
1	Course Title:	MULTI-S	ENSOR DATA FUSION							
2	Course Code:	BM5140								
3	Type of Course:	Optional								
4	Level of Course:	Second	Cycle							
5	Year of Study:	1								
6	Semester:	2								
7	ECTS Credits Allocated:	6.00								
8	Theoretical (hour/week):	3.00								
9	Practice (hour/week):	0.00								
10	Laboratory (hour/week):	0								
11	Prerequisites:	Undergraduate Level Probability and Statistics Knowledge								
12	Language:	Turkish								
13	Mode of Delivery:	Face to face								
14	Course Coordinator:	Prof. Dr. KEMAL FİDANBOYLU								
15	Course Lecturers:	-								
16	Contact information of the Course Coordinator:	e-posta: kfidan@uludag.edu.tr Uludağ Üniversitesi, Bilgisayar Mühendisliği Bölümü Görükle Kampüsü, 16059 Nilüfer, Bursa								
17	Website:									
18	Objective of the Course:	To provide the students with knowledge about basic principles and applications of multi-sensor data fusion.								
19	Contribution of the Course to Professional Development:	Engineering Science: 85%; Engineering Design: 15%								
20	Learning Outcomes:									
		1	Define multi-sensor data fusion strategies							
		2	Classify different types of sensors							
		3	Describe the architectures of fusion networks							
		4	Explain several sensor representational formats such as spatial alignment, temporal alignment, semantic alignment and radiometric normalization							
		5	Examine Bayesian inference methods							
		6	Investigate different concepts of parameter estimation							
		7	Explain the principles of robust parameter estimation							
		8	Examine different sequential Bayesian interfaces such as recursive filters, Kalman filters, particle filters and multi- sensor multi-temporal data fusion							
		9	Discuss different approaches for pattern recognition							
		10	Explain the fundamentals of ensemble learning and sensor management							
21	Course Content:									
		Co	ourse Content:							
Week	Theoretical		Practice							
1	Introduction: Multi-sensor data fusion strategies; Formal framework; Catas fusion; Organization.	n strophic								

2	Sensors: Smart sensors; Logical sen Interface file systems; Sensor observ	sors; vation;							
3	Architecture: Fusion mode: Simple F	usion							
	networks; Network topologies.								
4	Common Representation Format: Sp temporal transformation; Geographic information system; Common representational format; Subspace m Multiple training sets.	atial al nethods;							
5	Spatial Alignment: Image registration information; Optical flow; Feature bas image registration; Resample/Interpor Pairwise transformation; Uncertainity estimation; Image fusion; Mosaic ima	; Mutual sed plation; ages.							
6	Temporal Alignment: Dynamic time v Dynamic programming; One sided dy time warping algorithm; Multiple time	varping; /namic series.							
7	Semantic Alignment: Assignment ma Clustering algorithm; Clustering ense	trix; mbles.							
8	Radiometric Normalization: Scales of measurement; Degree of similarity so Radiometric normalization functions; Binarization; Parametric normalizatio functions; Fuzzy normalization function Ranking; Conversion to probabilities.	f cales; n ons;							
9	Bayesian Inference: Bayesian analys	sis;							
Activit	es		Number	Duration (hour)	Total Work Load (hour)				
Theore	iviaximum likelinood; Least squares; lical Guassian model: Generalized Millma	Linear	14	3.00	42.00				
Practica	als/Labs		0	0.00	0.00				
Se ^l f ¹ stu	Robust Statistics: Outliers; Robust pa	arameter	14	5.00	70.00				
Homew	vorks		1	33.00	33.00				
Project	subspace in computer vision.		0	0.00	0.00				
Field S	tudies		0	0.00	0.00				
Midtern	Robanssubspace techniques; Robus	t	1	15.00	15.00				
Others			0	0.00	0.00				
Final E	Recognition; Naive Bayes' classifer; V	/ariants;	1	20.00	20.00				
Total W	/ork Load				180.00				
Tojal w	ork load/30 hr Ensemble Learning: Bayesian frame	work:			6.00				
ECTS (Credit of the Course				6.00				
	Diversity measures; Classifier types; Combination strategies; Simple combination strategies; Simple combination; Boosting. Sensor Management: Hierarchical Classification; Sensor management techiques.	piners;							
22	Textbooks, References and/or Other Materials:		H.B. Mitchel, Data Fusion: Concepts and Ideas, 2nd Ed., Springer-Verlag 2012.						
23	Assesment								
TERM L	EARNING ACTIVITIES	NUMBE R	WEIGHT						
Midtern	n Exam	1	20.00						
Quiz		0	0.00						
Home v	work-project	1	20.00						
L									

Final Exam 1							60	60.00								
Total 3								10	100.00							
Contribution of Term (Year) Learning Activities to Success Grade							40	40.00								
Contribution of Final Exam to Success Grade							60	60.00								
Total								10	100.00							
Measurement and Evaluation Techniques Used in the Course							ne Cla mio sin rela	Classical problem-solving ability will be measured in midterm and final exams. The project will include research, simulation, report writing and presentation on a subject related to the course content.								
24 ECTS / WORK LOAD TABLE																
25 CONTRIBUTION OF LEARNING OUTCOMES TO PROGRAMME QUALIFICATIONS																
	PQ1	PQ2	PQ3	PQ4	PQ5	PQ6	PQ7	PQ8	PQ9	PQ1 0	PQ11	PQ12	PQ1 3	PQ14	PQ15	PQ16
ÖK1	5	3	3	2	2	2	0	0	0	0	0	0	0	0	0	0
ÖK2	5	4	4	2	2	2	0	0	0	0	0	0	0	0	0	0
ÖK3	5	4	4	2	2	2	0	0	0	0	0	0	0	0	0	0
ÖK4	5	4	4	2	2	2	0	0	0	0	0	0	0	0	0	0
ÖK5	5	4	4	2	2	2	0	0	0	0	0	0	0	0	0	0
ÖK6	5	4	4	2	2	2	0	0	0	0	0	0	0	0	0	0
ÖK7	5	4	4	2	2	2	0	0	0	0	0	0	0	0	0	0
ÖK8	5	4	4	2	2	2	0	0	0	0	0	0	0	0	0	0

4 High

5 Very High

ÖK9

ÖK10

Contrib

ution Level: 1 very low

2 low

LO: Learning Objectives PQ: Program Qualifications

3 Medium