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Eğitim Bilgileri

Doktora, The University of Nottingham, Department Of Electrical And Electronics Eng., Birleşik Krallık 1988 - 1993

Yüksek Lisans, İstanbul Teknik Üniversitesi, Fen Bilimleri Enstitüsü, Elektronik Ve Haberleşme Mühendisliği Anabilim

Dalı, Türkiye 1984 - 1987

Lisans, İstanbul Teknik Üniversitesi, Elektrik Fakültesi, Enerji Pr., Türkiye 1980 - 1984

Yabancı Diller

İngilizce

Yaptığı Tezler

Doktora, Real-Time Identification of Rbot Dynamics Model Parameters Using Parallel Processing, The University Of Nottingham, Department Of Electrical And Electronics Eng., 1993

Yüksek Lisans, Ters kinematik çözüm ve yeni bir robot kontrol dili önerilmesi , İstanbul Teknik Üniversitesi, Fen Bilimleri Enstitüsü, Elektronik Ve Haberleşme Mühendisliği Anabilim Dalı, 1987

Araştırma Alanları

Teknik Bilimler, Bilgi Sistemleri, Haberleşme ve Kontrol Mühendisliği, Kontrol ve Sistem Mühendisliği, Durum

Gözleyicileri ve Kestirim, Kesikli Zaman Sistemleri ve Bilgisayarla Kontrol , Robotik ve Mekatronik Sistemler, Alan ve

Servis Robotları, Mekatronik Sistemler, Rota ve Hareket Planlama

Akademik Unvanlar / Görevler

Prof.Dr., İstanbul Teknik Üniversitesi, Elektrik-Elektronik, Kontrol Ve Otomasyon Mühendisliği, 1985 - Devam Ediyor

Doç.Dr., İstanbul Teknik Üniversitesi, Elektrik-Elektronik, Kontrol Ve Otomasyon Mühendisliği, 1998 - 2006

Yrd.Doç.Dr., İstanbul Teknik Üniversitesi, Elektrik-Elektronik, Kontrol Ve Otomasyon Mühendisliği, 1996 - 1998

Araştırma Görevlisi, İstanbul Teknik Üniversitesi, Elektrik-Elektronik, Kontrol Ve Otomasyon Mühendisliği, 1985 - 1996

Akademik İdari Deneyim

Bölüm Başkanı, İstanbul Teknik Üniversitesi, Elektrik-Elektronik, Kontrol Ve Otomasyon Mühendisliği, 2020 - Devam Ediyor

Bölüm Başkanı, İstanbul Teknik Üniversitesi, Elektrik-Elektronik, Kontrol Ve Otomasyon Mühendisliği, 2017 - 2020

Fakülte Akademik Kurul Üyesi, İstanbul Teknik Üniversitesi, Elektrik-Elektronik, Kontrol Ve Otomasyon Mühendisliği, 2015 - 2018

İstanbul Teknik Üniversitesi, Elektrik-Elektronik Fakültesi, Elektrik Mühendisliği Bölümü, 2008 - 2009

Fakülte Kurulu Üyesi, İstanbul Teknik Üniversitesi, Elektrik-Elektronik, Kontrol Ve Otomasyon Mühendisliği, 2003 - 2006

İstanbul Teknik Üniversitesi, Elektrik-Elektronik Fakültesi, 1999 - 2001

Verdiği Dersler

INTRODUCTION TO ROBOTICS, Lisans, 2016 - 2017, 2015 - 2016, 2014 - 2015, 2013 - 2014, 2012 - 2013, 2011 - 2012, 2010 - 2011, 2009 - 2010, 2008 - 2009, 2007 - 2008, 2006 - 2007, 2005 - 2006, 2004 - 2005

PROBABİLİSTİC METHODS IN ROBOTICS, Doktora, 2016 - 2017, 2015 - 2016, 2014 - 2015, 2013 - 2014, 2012 - 2013, 2011 - 2012

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- I. **Reference cage architecture for autonomous docking of mobile robots in automotive production systems**
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- II. **A histogram-based sampling method for point cloud registration**
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- III. **3D generalized bias compensated pseudolinear Kalman filter for colored noisy bearings-only measurements**
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- IV. **A precise scan matching based localization method for an autonomously guided vehicle in smart factories**
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- V. **Improving Navigation Stack of a ROS-Enabled Industrial Autonomous Mobile Robot (AMR) to be Incorporated in a Large-Scale Automotive Production**
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- VI. **Robust affine registration method using line/surface normals and correntropy criterion**
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COMPLEX & INTELLIGENT SYSTEMS, cilt.8, ss.1-19, 2022 (SCI-Expanded)
- VII. **Generalized bias compensated pseudolinear Kalman filter for colored noisy bearings-only measurements**
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- VIII. **Integration of affine ICP into the precise localization problem of smart-AGVs: Procedures, enhancements and challenges**
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- IX. **Guided Soft Actor Critic: A Guided Deep Reinforcement Learning Approach for Partially Observable Markov Decision Processes**
Haklıdır M., Temeltaş H.
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- X. **Evaluation of 3D LiDAR Sensor Setup for Heterogeneous Robot Team**
Haddeler G., Aybakan A., Akay M. C., Temeltaş H.
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- XI. **Constructing common height maps with various entropy-based similarity metrics and utilizing layering method for heterogeneous robot teams**
Akay M. S., Temeltaş H.
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- XII. **Multi-Robot Energy-Efficient Coverage Control with Hopfield Networks**
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- XIII. **Exact flow of particles using for state estimations in unmanned aerial systems' navigation**
Duymaz E., Oguz A. E., Temeltaş H.
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- XIV. **Anticipatory Control of Momentum for Bipedal Walking on Uneven Terrain**
Darici O., Temeltaş H., Kuo A. D.
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- XV. **Multi-Robot Workspace Allocation with Hopfield Networks and Imprecise Localization**
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- XVI. **Self-adaptive Monte Carlo method for indoor localization of smart AGVs using LIDAR data**
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- XVII. **Optimal regulation of bipedal walking speed despite an unexpected bump in the road**
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- XVIII. **A quantized approach for occupancy grids for autonomous vehicles: Q-Trees**
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- XIX. **Patterns of approximated localised moments for visual loop closure detection**
Erhan C., Sariyanidi E., Sencan O., Temeltaş H.
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- XX. **Particle flow filter as a novel state estimation method for simultaneous localization and mapping problem**
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- XXII. **A Fast and Robust Feature-Based Scan-Matching Method in 3D SLAM and the Effect of Sampling Strategies**
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- XXIII. **3D Multi-Layered Normal Distribution Transform for Fast and Long Range Scan Matching**
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- XXV. **FEATURE-BASED 3D OUTDOOR SLAM WITH LOCAL FILTERS**
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- XXVI. **A new formulation method for solving kinematic problems of multiarm robot systems using quaternion algebra in the screw theory framework**
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- XXVII. **Performance Analysis of Numerical Integration Methods in the Trajectory Tracking Application of Redundant Robot Manipulators**
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- XXVIII. **Using Linde Buzo Gray Clustering Neural Networks for Solving the Motion Equations of a Mobile Robot**
Aydin S., Kilic I., Temeltas H.
ARABIAN JOURNAL FOR SCIENCE AND ENGINEERING, cilt.36, sa.5, ss.795-807, 2011 (SCI-Expanded)
- XXIX. **A Comparative Study of Three Inverse Kinematic Methods of Serial Industrial Robot Manipulators in the Screw Theory Framework**
Sariyildiz E., Cakray E., Temeltaş H.
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- XXX. **Dynamical Modeling of Cooperating Underactuated Manipulators for Space Manipulation**
Yesiloglu S. M., Temeltaş H.
ADVANCED ROBOTICS, cilt.24, sa.3, ss.325-341, 2010 (SCI-Expanded)
- XXXI. **Behavioral task processing for cognitive robots using artificial emotions**
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- XXXII. **SLAM for Robot Navigation**
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- XXXIII. **Decoupled approach to integrated optimum design of structures and robust control systems**
BOZCA M., MUGAN A., Temeltaş H.
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- XXXIV. **A new approach to map building by sensor data fusion: sequential principal component-SPC method**
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- XXXV. **State observation for elastoplastic friction models in positioning systems by utilizing Leunberger observers**
Temeltas H., AKTAS G.
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- XXXVI. **Hardware in the loop robot simulators for on site and remote education in robotics**
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- XXXVIII. **REAL-TIME IDENTIFICATION OF ROBOT - DYNAMIC PARAMETERS USING PARALLEL-PROCESSING .2. IMPLEMENTATION AND TESTING**
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Diğer Dergilerde Yayınlanan Makaleler

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Sencan O., Temeltaş H.
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- II. **Power Aware Adaptive Coverage Control with Consensus Protocol**
Turanli M., TEMELTAŞ H.
Journal of Automation and Control Engineering, cilt.4, sa.6, ss.383-388, 2016 (Hakemli Dergi)
- III. **Adaptive Coverage Control with Power Aware Control Laws and Exponential Forgetting**
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- IV. **Multi Agent Coverage Control with Bounded Gain Forgetting Composite Adaptive Controller**
Turanli M., TEMELTAŞ H.
International Journal of Electrical, Computer, Energetic, Electronic and Communication Engineering, cilt.10, sa.12, ss.1406-1413, 2016 (Hakemli Dergi)
- V. **A Dynamic Simulator Design for Humanoid Robots**
Saiyildiz E., TEMELTAŞ H.
International Journal of Engineering Science and Innovative Technology (IJESIT), cilt.4, sa.6, ss.8-19, 2015 (Hakemli Dergi)
- VI. **GENİŞLETİLMİŞ KALMAN FİLTRESİ GKF TABANLI UÇAK ÜZERİ EŞ ZAMANLI KONUMLAMA VE HARİTALAMA U EZKH**
OĞUZ A. E., TEMELTAŞ H.
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- VII. **Potential field based navigation task for autonomous flight control of unmanned aerial vehicles**
Cetin O., KURNAZ S., Kaynak O., TEMELTAŞ H.
International Journal of Automation and Control, cilt.5, sa.1, ss.1-21, 2011 (Scopus)
- VIII. **SENSÖR VERİSİ BİRLEŞTİRME TEKNİKLERİ VE HEDEF İZLEME SİSTEMİNE UYGULANMASI**
DOKUMACI N., TEMELTAŞ H.
Havacılık ve Uzay Teknolojileri Dergisi, cilt.4, sa.3, ss.33-40, 2010 (Hakemli Dergi)
- IX. **DİKEY İNİŞ KALKIŞ YAPABİLEN DÖRT ROTORLU HAVA ARACININ QUADROTOR UÇUŞ KONTROLÜ**
DİKMEN İ. C., ARISOY A., TEMELTAŞ H.
Havacılık ve Uzay Teknolojileri Dergisi, cilt.4, sa.1, ss.77-87, 2010 (Hakemli Dergi)
- X. **Flight control of a VTOL air vehicle**

I Can D., ARISOY A., TEMELTAŞ H.

JOURNAL OF AERONAUTICS AND SPACE TECHNOLOGIES, cilt.4, sa.3, ss.33-40, 2010 (Hakemli Dergi)

XI. OPTİK AKIŞIN HESAPLANMASI VE YAPAY SİNİR AĞLARI İLE YORUMLANARAK MOBİL ROBOTLAR İÇİN ENGEL TESPİTİ VE KAÇINMA DAVRANIŞINDA KULLANILMASI

DUR E., TEMELTAŞ H., KURNAZ S.

Havacılık ve Uzay Teknolojileri Dergisi, cilt.4, sa.1, ss.77-87, 2009 (Hakemli Dergi)

Kitap & Kitap Bölümleri

I. Planar-Feature Based 3D SLAM Using Randomized Sigma Point Kalman Filters

ULAŞ C., TEMELTAŞ H.

Advances in Estimation Navigation and Spacecraft Control, Daniel Choukroun, Yaakov Oshman, Julie Thienel, Moshe Idan, Editör, Springer, ss.119-134, 2015

II. Formation graphs and decentralized formation control of multi vehicles with kinematics constraints

Sisli U., TEMELTAŞ H.

Springer Tracts in Advanced Robotics, Herman Bruyninckx, Libor Přebí, Miroslav Kulich, Editör, Springer, ss.93-101, 2008

Hakemli Kongre / Sempozyum Bildiri Kitaplarında Yer Alan Yayınlar

I. Autonomous Driving Systems for Decision-Making Under Uncertainty Using Deep Reinforcement Learning Derin Pekıştirmeli Öğrenme Kullanan Belirsizlik Altında Karar Verme Odaklı Otonom Sürüş Sistemleri

Haklidiir M., Temeltaş H.

30th Signal Processing and Communications Applications Conference, SIU 2022, Safranbolu, Türkiye, 15 - 18 Mayıs 2022

II. Feasibility Analysis of Path Planning Algorithms

Allozi E., Yılmaz A., Ervan O., Temeltaş H.

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III. An Autonomous Robotic System for Ground Surface and Subsurface Imaging

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8th International Conference on Engineering and Emerging Technologies, ICEET 2022, Kuala-Lumpur, Malezya, 27 - 28 Ekim 2022

IV. Fuzzy Controlled Adaptive Follow the Gap Obstacle Avoidance Algorithm

Yücel B., YILMAZ A., ERVAN O., TEMELTAŞ H.

7th International Conference on Robotics and Artificial Intelligence (ICRAI 2021), Guangzhou, Çin, 19 - 22 Kasım 2021

V. Tensor Voting Based 3-D Point Cloud Processing for Downsampling and Registration

ERVAN O., TEMELTAŞ H.

2020 6th International Conference on Robotics and Artificial Intelligence, 20 - 22 Kasım 2020

VI. Robust Affine Iterative Closest Point Variant Using Point-to-line Metric and Correntropy Criterion

YILMAZ A., TEMELTAŞ H.

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VII. ROS Architecture for Indoor Localization of Smart-AGVs Based on SA-MCL Algorithm

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- VIII. **AFFINE ICP FOR FINE LOCALIZATION OF SMART-AGVS IN SMART FACTORIES**
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- IX. **A 3D LiDAR Dataset of ITU Heterogeneous Robot Team**
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- X. **Multi-Robot Collaborative Coverage Under Localization Uncertainty**
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- XI. **An Improvement on SA-MCL Algorithm: Ellipse Based Energy Grids**
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- XII. **Downsampling of a 3D LiDAR Point Cloud by a Tensor Voting Based Method**
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- XIII. **Map Matching Performance under Various SimilarityMetrics for Heterogeneous Robot Teams**
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- XV. **Bird Eye View Transformation for 3D LIDAR Data in Real Time**
Al Mamun A., Aybakan A., TEMELTAŞ H.
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- XVI. **Kendinden Uyarlamalı Monte Carlo Konumlama Algoritması için Elips Tabanlı Yeni Bir Enerji Hesap Yöntemi ve Akıllı AGV'lere Uygulaması**
YILMAZ A., TEMELTAŞ H.
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- XVII. **Otonom Liman Operasyonlarında Otomatik Yönlendirilmiş Araç Kullanımı: Terminal Çekicisi ile Yön Bulma Algoritması Karşılaştırma Çalışması**
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- XVIII. **Workspace Allocation for Team of Robots with Different Actuation Capabilities**
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- XIX. **Feature extraction of EMG signals, classification with ANN and kNN algorithms**
Cerci C., TEMELTAŞ H.
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- XX. **Real-time visual loop closure detection for unmanned aerial vehicles**
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- XXI. **A Real-Time Localization Method For AGVs In Smart Factories**
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- XXII. **Adaptive Coverage Control with Guaranteed Power Voronoi Diagrams**
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- XXIII. **MECHANICAL CONSEQUENCES OF STEPPING ON AN UNANTICIPATED BUMP WHILE WALKING**
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- XXIV. **ANTICIPATORY SPEED CHANGES FOR OPTIMAL HUMAN WALKING ON UNEVEN TERRAIN**
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- XXV. **Efficient visual loop closure detection in different times of day**
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- XXVI. **Transversal Positioned (TRAP) 2D Laser Range Finder Configuration**
Ervan O., Sencan O., Temeltaş H.
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- XXVII. **Diyagonal 2 Boyutlu Lazer Yerleşimi d2Bly Algoritması**
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- XXVIII. **Ters Sarkaç Kendini Dengeleyen Robot**
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- XXIX. **Power Aware Adaptive Coverage Control with Consensus Protocol**
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- XXX. **Sliding Mode Control of the Simplest Walking Model**
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- XXXI. **Beware of the bump Optimal strategy to traverse a stepheight perturbation**
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Akademi Dışı Deneyim

Altınay Robtik ve Otomasyon Sis.
GENELKURMAY BAŞKANLIĞI
The University of Nottingham