

UAV Autonomous Landing

Team Expeditus

SDSMT MCS

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Introduction

UAV Autonomous Landing Project

Team Expeditus

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Sponsor

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Goal

Demonstrate the capability of a UAV to autonomously take-off, navigate through some waypoints, return to the landing pad, and land with a minimum of distance and orientation error.

Requirements

Goal

- receive a set of waypoints
- autonomously take-off
- navigate through waypoints
- return to launch pad
- **land with $\pm .1$ distance and $\pm 15^\circ$ orientation error**

Limitations

- landing platform is a fixed position
- landing platform is a stable, horizontal surface
- environment is ideal(no wind, gps available, no obstacles)

User Stories/Backlog

- **User 1(U-1):**

As a user, I want to communicate the waypoints to the UAV.

- **Owner 1(O-1):**

As an owner, I want the UAV to autonomously take-off from the landing pad.

- **Owner 2(O-2):**

As an owner, I want the UAV to autonomously navigate through a set of waypoints.

- **Owner 3(O-3):**

As an owner, I want the UAV to autonomously return to the location of the landing pad.

- **Owner 4(O-4):**

As an owner, I want the UAV to autonomously land on the landing pad without damaging the craft.

- **Owner 5(O-5):**

As an owner, I want the UAV to autonomously land on the landing pad with the correct orientation.

As a user, I want to communicate the waypoints to the UAV.

Task No.	Task	Date Completed	Sprint
1	Review previous method/interface for communicating coordinates to UAV.	10/05/15	1
2	Review code that communicates with quadrotor	10/16/15	2
3	Review code that allows a user to input waypoints	10/16/15	2

As an owner, I want the UAV to autonomously take-off from the landing pad.

Task No.	Task	Date Completed	Sprint
1	Review previous implementation for autonomous take-off.	10/05/15	1
2	Review code that enables the quadrotor to autonomously take-off from landing pad	10/16/15	2

As an owner, I want the UAV to autonomously navigate through a set of waypoints.

Task No.	Task	Date Completed	Sprint
1	Review previous implementation for navigating waypoints.	10/05/15	1
2	Review code that enables the quadrotor to autonomously navigate through a series of way-points	10/16/15	2

As an owner, I want the UAV to autonomously return to the location of the landing pad.

Task No.	Task	Date Completed	Sprint
1	Review previous implementation to autonomously return to location of landing pad	10/05/15	1
2	Review code that allows the autonomous return of the UAV to the landing pad.	10/16/15	2

As an owner, I want the UAV to autonomously land on the landing pad without damaging the craft

Task No.	Task	Date Completed	Sprint
1	Review previous implementation for autonomous landing	10/05/15	1
2	Install previous implementation	10/19/15	2
3	Test previous implementation	10/26/15	2

As an owner, I want the UAV to autonomously land on the landing pad with the correct orientation.

Task No.	Task	Date Completed	Sprint
1	Review previous implementation for autonomous landing	10/05/15	1
2	Install previous implementation	10/19/15	2
3	Test previous implementation	10/26/15	2

Initial Common Tasks

Task No.	Task	Date Completed	Sprint
1	Install Ubuntu 14.04 or some other ROS Indigo/Jade distro compliant OS.	09/25/15	1
2	Setup Gazebo 6.+	09/25/15	1
3	Download Rviz package	09/25/15	1
4	Setup Simulation Environment	11/02/15	2

C Continued

Initial Common Tasks

Task No.	Task	Date Completed	Sprint
5	Review previous iteration of project documentation	09/25/15	1
6	Inspect current quadrotor configuration	09/28/2015	2
7	Identify parts needed for quadrotor	11/02/2015	2
8	Acquire parts needed for hexrotor	12/01/2015	3

Sprint 1 - Successes

- Revised project scope
- Product Backlog - User Stories
- Setup Development Environment
- Review previous years hardware and software

Sprint 1 - Setbacks

- Previous years UAV unusable
- Previous years flight code unusable

Sprint 2 - Successes

- Visual Homography Code repurposed
- Created simulation environment
- Ordered parts for new Hex-copter

Sprint 2 - Setbacks

- Simulation only supports manual control

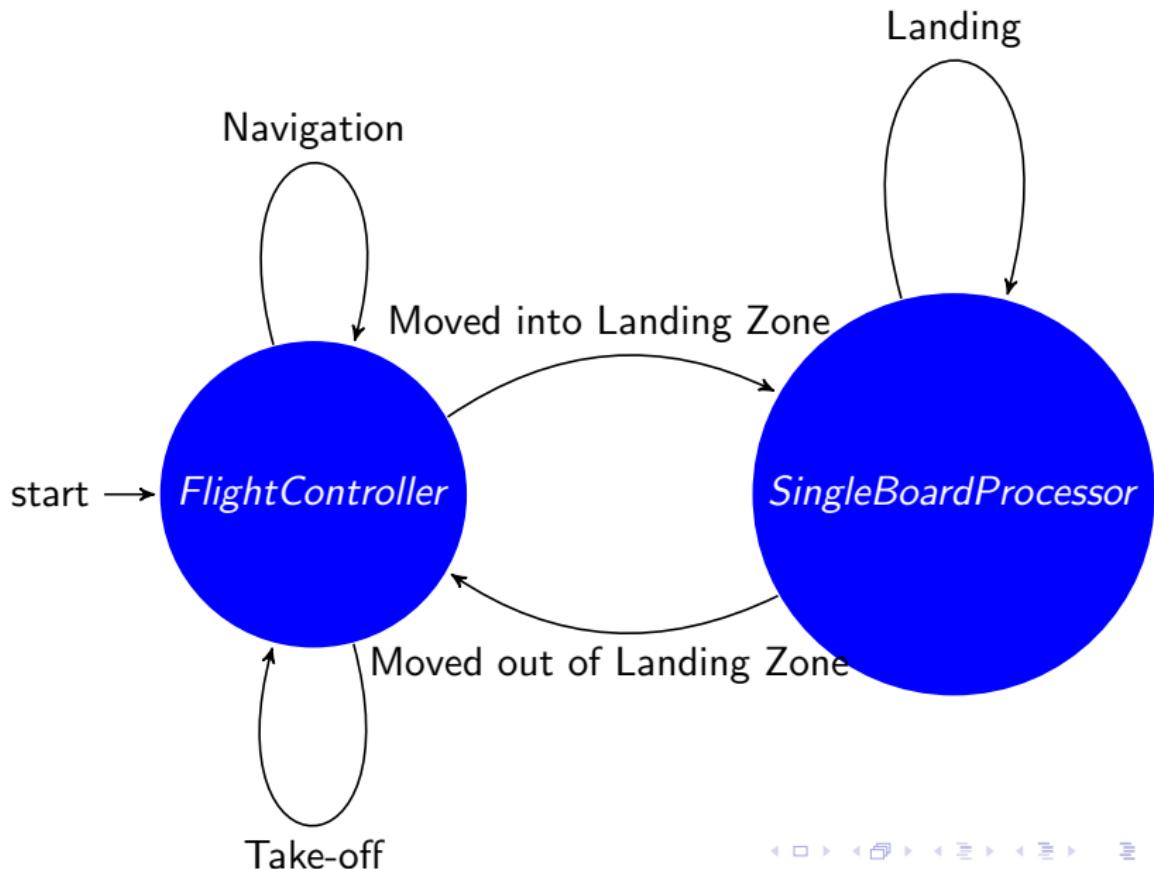
Sprint 3 - Successes

- Assembled Frame, Motors, ESC's
- Many SITL simulations
- Waypoint Publisher publishes mavros commands
- Working image homography code
- Becoming familiar with python openCV libraries

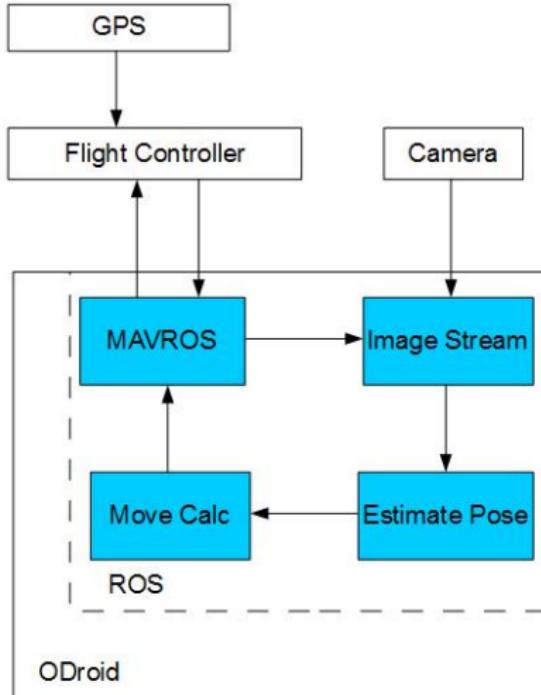
Sprint 3 - Setbacks

- Pixhawk delayed 2 weeks, build not completed
- SITL simulations rejected waypoint files
- SITL simulations rejected mavros commands

Design



Architecture



Hardware Requirements

- ODroid XU4
- Pixhawk Flight Controller
- GPS peripheral
- Camera
- Battery
- UAV(Frame, Motors, ESCs, Power Distribution Board)

Software Requirements

- Mavlink
- OpenCV
- Robot Operating System(ROS) Indigo/Jade Distro
- Ubuntu 14.04

UAV Design & Tech Specs

Physical design of the hex-copter is the **Turnigy Talon Hexcopter**



Visual Homography Design & Tech Specs

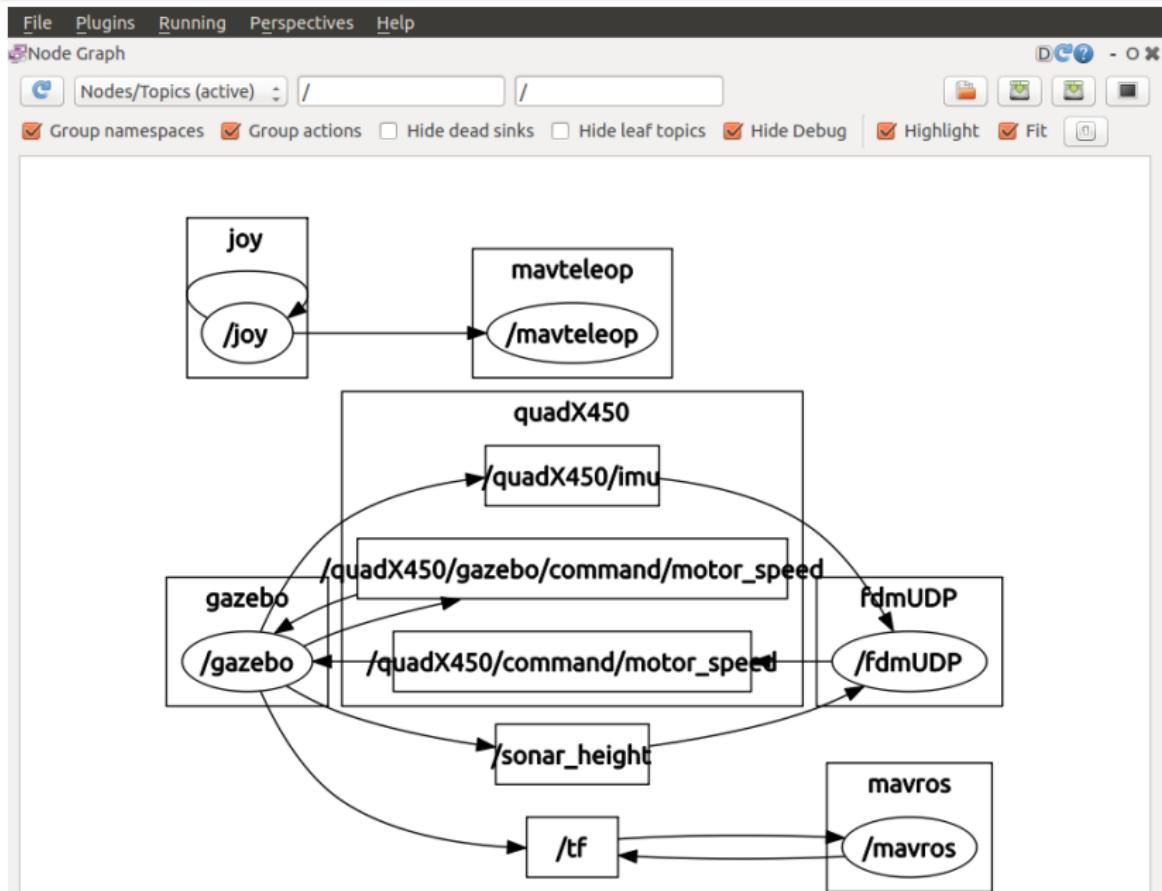
Design & Tech

- Sarsa
- 2D State Space
- 3D State Space

Setbacks

- Research and familiarizing
- Simulation Environment

Simulation Design & Tech Specs



As an owner, I want the UAV to autonomously take-off from the landing pad.

Task No.	Task	Testing
1	Review previous implementation for autonomous take-off.	Send mission containing takeoff followed by hover command in simulation.
2	Review code that enables the quadrotor to autonomously take-off from landing pad	Upload code to physical UAV and send mission containing takeoff followed by hover command with manual override enabled.

As an owner, I want the UAV to autonomously navigate through a set of waypoints.

Task No.	Task	Test
1	Review previous implementation for navigating waypoints.	Send mission containing takeoff followed by waypoints and once the last waypoint is reached a hover command all in simulation.
2	Review code that enables the quadrotor to autonomously navigate through a series of way-points	Upload code to physical UAV and send mission again with manual override enabled

As an owner, I want the UAV to autonomously return to the location of the landing pad.

Task No.	Task	Test
1	Review previous implementation to autonomously return to location of landing pad	The last waypoint from the previous test should be the landing pad but to verify a image match will be used in simulation that will verify that the UAV is in fact above the landing pad.
2	Review code that allows the autonomous return of the UAV to the landing pad.	The physical UAV will match what it sees with its camera to a image it has stored of the landing pad at multiple heights.

As an owner, I want the UAV to autonomously land on the landing pad without damaging the craft

Task No.	Task	Test
1	Review previous implementation for autonomous landing	Test to verify
2	Install previous implementation	Test to verify
3	Test previous implementation	Test to verify

Visual Homography Landing Testing - O-5

As an owner, I want the UAV to autonomously land on the landing pad with the correct orientation.

Task No.	Task	Test
1	Review previous implementation for autonomous landing	Test to verify
2	Install previous implementation	Test to verify
3	Test previous implementation	Test to verify

Integration - U-1

As a user, I want to communicate the waypoints to the UAV.

Task No.	Task	Test
1	Review previous method/interface for communicating coordinates to UAV.	Connect GPS to pixhawk and verify it receives a connection and in Mavros verify we can retrieve gps coordinates from gps in ROS.
2	Review code that communicates with quadrotor	Verify that all commands in Mavros can be sent to and accepted by the Pixhawk and it acts appropriately
3	Review code that allows a user to input waypoints	Verify that user entered waypoints can be uploaded into Pixhawk Successfully with mavros.



Remaining Backlog

- **User 1(U-1)**
- **Owner 1(O-1)**
- **Owner 2(O-2)**
- **Owner 3(O-3)**
- **Owner 4(O-4)**
- **Owner 5(O-5)**
- **Common**

Revised Goals

Project Goals remain fixed

Risk Analysis

- Simulation: SITL has proven to be problematic
- UAV Build: Borrowing items from UAV Team (Radio and Control)
- UAV Build: One UAV for physical testing and demonstration
- Landing Algorithm: Many approaches, we may pick the wrong one

- Simulation:
 - Attempt HIL as Alternative
- UAV Build(Sharing)
 - Schedule use of tools to prevent conflict
 - Request more funding if schedule is untenable
- UAV Build(One Shot)
 - Integrate manual control override
 - Validate solutions through simulation

Sprint 3.5 12/16/15 to 1/10/16

- Finish UAV Build(C)
- Manual Flight of UAV(C)
- Autonomous Flight of UAV(C,U-1,O-1,O-2,O-3)
- Resolve Simulation Issues(C)

At the end of break, 3 backlog items will have been completed

Sprint 4 1/18/16 2/5/16

- Finish Landing Algorithm Simulations(O-4,O-5)

At the end of sprint 4, we should have a landing approach validated by simulation.

Timeline...continued

Sprint 5 2/15/16 3/4/16

- Integration of Landing Autonomy on UAV(O-4,O-5)

At the end of sprint 5, we should have completed the remainder of backlog items.

Sprint 6 3/21/16 4/15/16

- Refinement

At the end of sprint 6, project will be complete

Budget

Item	Qty	Price	Total
Frame	1	\$79.99	\$79.99
Motors	8	\$23.99	\$191.92
ESCs	8	\$17.78	\$142.24
Pixhawk	1	\$199.99	\$199.99
Power Distribution	1	\$19.99	\$19.99
GPS Mast	2	\$10.00	\$20.00
GPS	2	\$89.99	\$179.98
Power Module	1	\$24.99	\$24.99
Odroid XU4	1	\$75.95	\$75.95
Props(set of 4)	3	\$7.55	\$22.65
TOTAL			\$957.70

Intellectual Property:
Project is owned by SDSMT

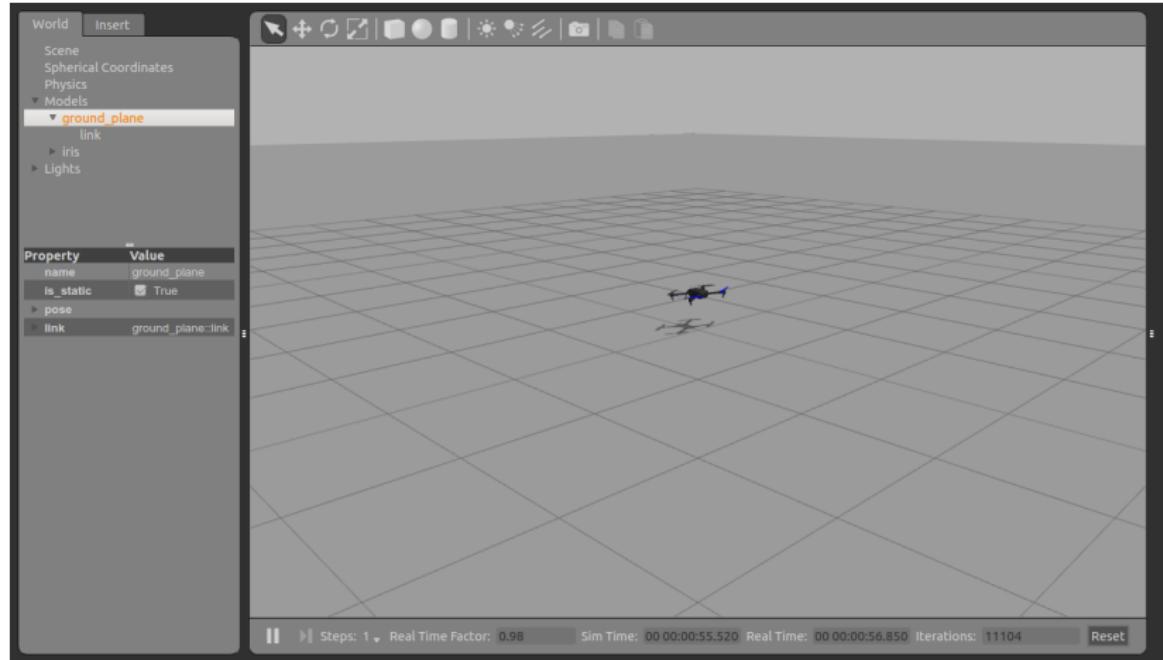
Licensing for Dependencies:

- OpenCV: BSD
- ROS: BSD
- Mavlink: LGPL version 3
- QGroundControl: GPL version 3

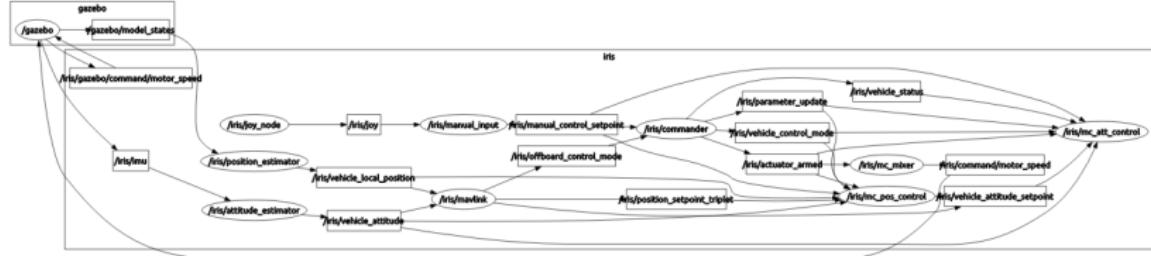
Demos

- PX4 ROS SITL
- Ground Control Station
- Visual Homography

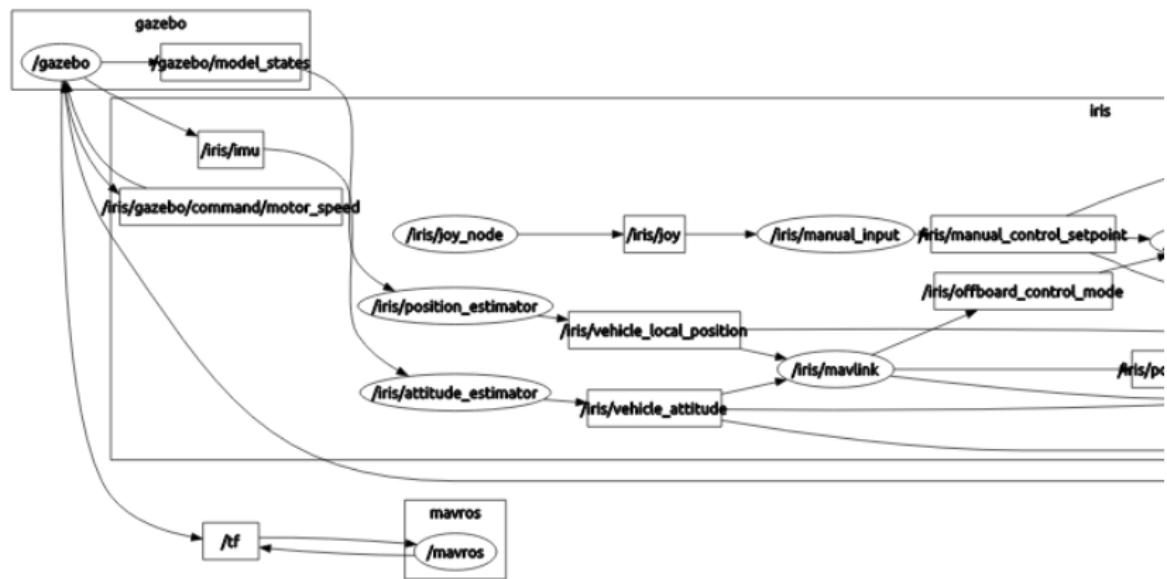
Simulation - PX4 ROS SITL



PX4 ROS SITL...continued



PX4 ROS SITL...continued

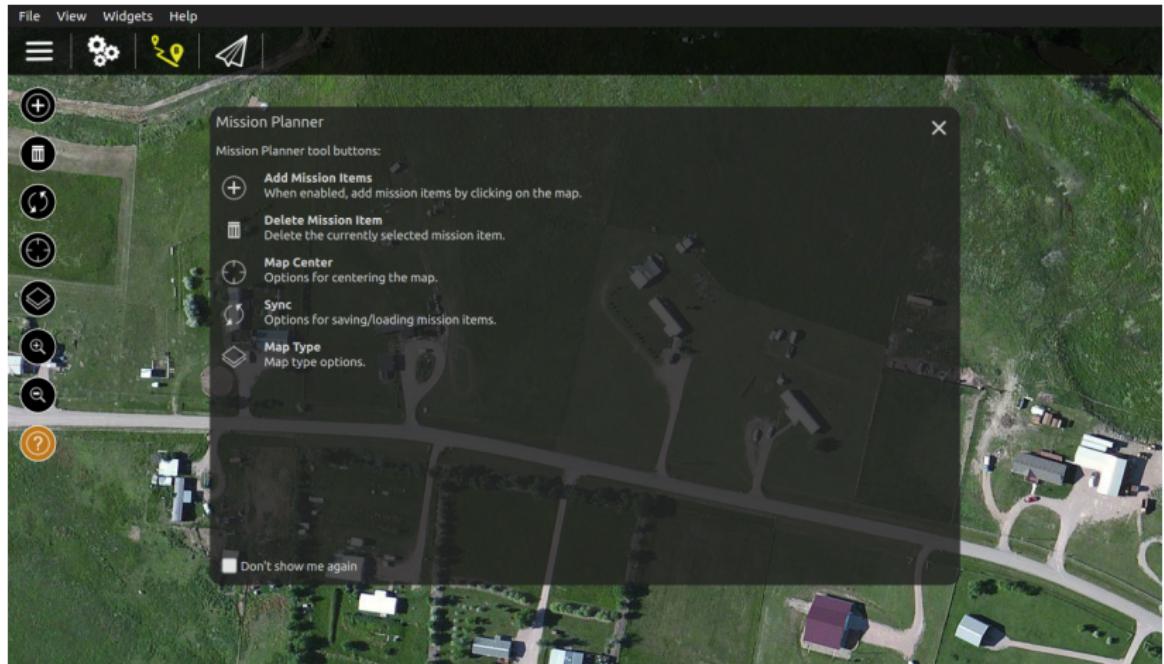


PX4 ROS SITL...continued

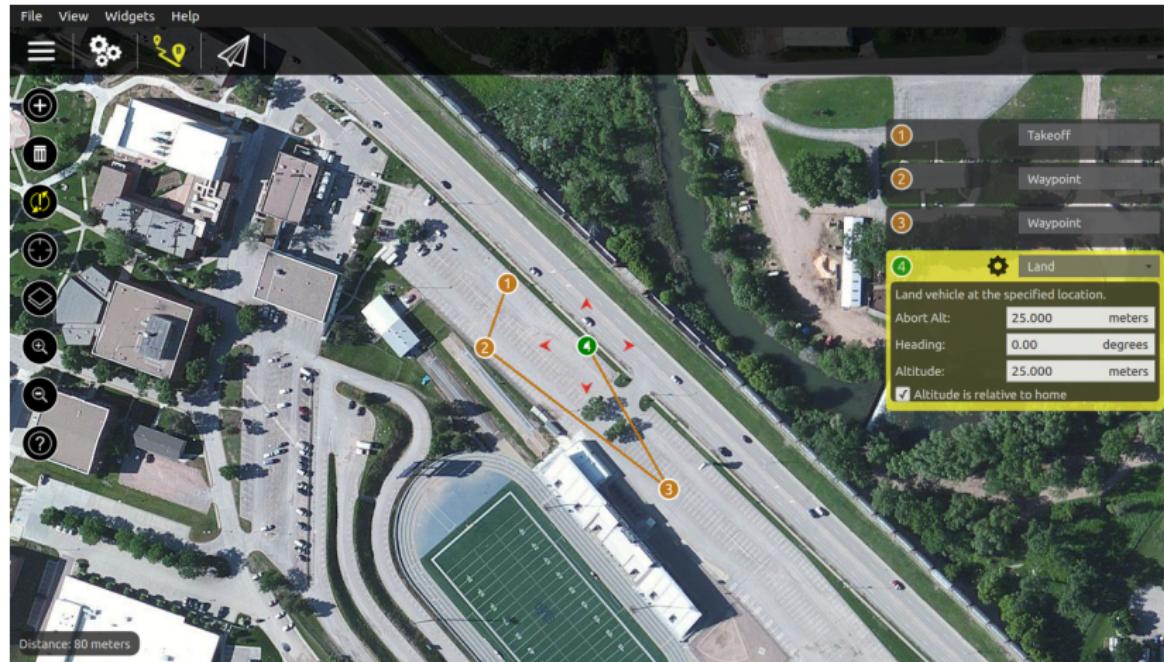
Ground Control Station - QGroundControl



Ground Control Station...continued

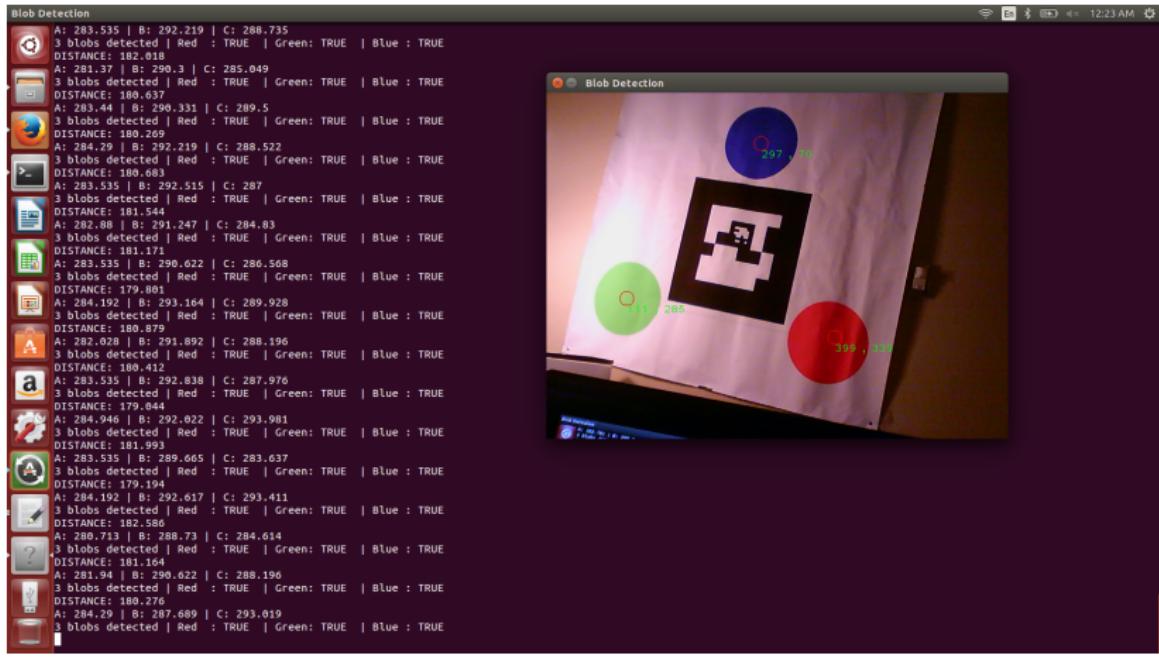


Ground Control Station...continued



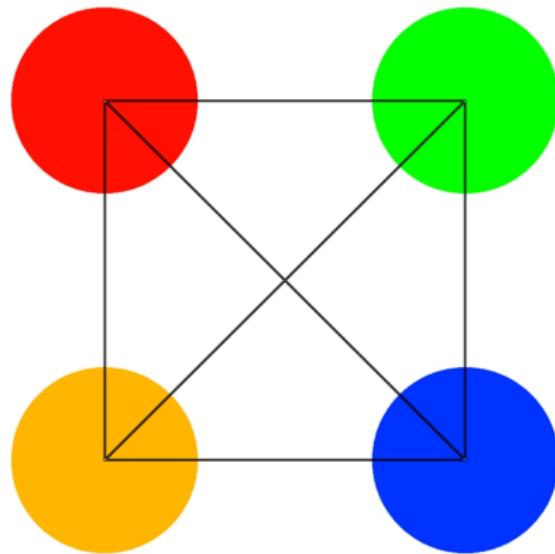
Vision-Based Landing

- Began playing with last year's code
- Able to detect three blobs and distance to target



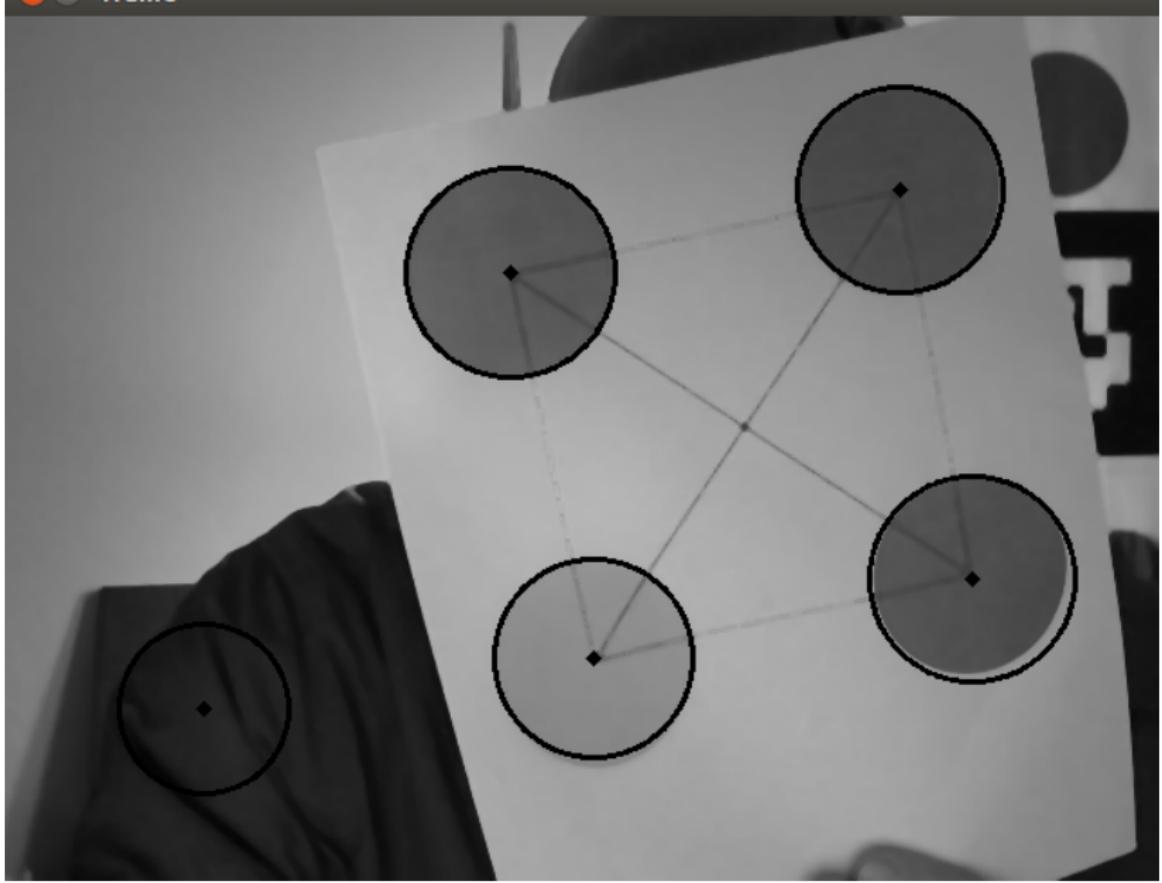
Vision-Based Landing...continued

- After our computer vision class, we considered adding a fourth circle
- This gives us a square target instead of triangle





frame



END

Questions