
Towards indoor and outdoor accurate flying using AutoQuad



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Bachelor Thesis

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June 1, 2016

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Todo list

: A bachelors thesis (15 ECTS) report from a single student should have a length no more than 35 pages plus maximum 10 pages of appendices.	2
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Introduction: Indøres navigation http://innovationsfonden.dk/da/case/droner-rykker-indendoers-med-dansk	
Wireless communication module: 'footmotemark til at referere til samme fodnote flere gange	11
Debug/ISP: Refer to image of board	13
Test of WIFI range: Billede af pingtest	13
Test of WIFI range: figur af antal af valid crc pakker vs. distance	14
Test of WIFI range: Figure shows test from above	14
Scheduler: A little description about the scheduler implementation. Add tasks, and run the scheduler. Show how it waits for tick and the runs through all of the tasks that is in RUN state.	15
Scheduler: Add description of slip and crc task, maybe also spoof and node, not sure.. .	17
: Ændre 0:3 til 0:1 da en uint16_t kun tager 2 bytes og ikke 4	21
Indoor localization: insert image of markerLocator marker with different orders	25
: Dette er forkert, eftersom alle defines er taget fra AQ's can.h så der passer det.. . . .	38
: Fixe ref til section om GPS spoof	39
Initial test flight with spoofed GPS: Opdater billede med test-equipment	48
Comparison of onboard and spoofed GPS: Insert image from normal flight	53
Comparison of onboard and spoofed GPS: Gdop, skal den ikke være højere siden den har både vDOP, hDOP og tDOP	54
Comparison of onboard and spoofed GPS: Figure med gpgga plot	54
Comparison of onboard and spoofed GPS: Plot af northing and easting fra ukf	54
Comparison of onboard and spoofed GPS: plot af pos og switch samt dop så man kan se de ændrer sig ved skift.	55
Comparison of onboard and spoofed GPS: Billede der viser højden/hastigheden er mere woobly siden DOP er mega lav, den stoler for meget på GPS	55

Abstract

Until now drones keeps getting bigger and larger to carry bigger batteries with more capacity and to lift heavier payloads. This leads to drones getting less efficient, less responsive and gets more dangerous. Instead it has become popular to make drones smaller and increase the number of drones needed to solve a task.

(Materials & methods)

This thesis describes how to make three drones follow a leader drone with a preprogrammed path as an example of drones cooperating. A Linux PC running MarkerLocator tracks each drone's position and wirelessly transmits, using Xbee, the drone's positions to all drones. The position of each drone is spoofed into the drone using the CAN-bus and thereby overwriting the onboard GPS. An outdoor test has been made using the onboard GPS to test the leader-follower algorithm in a bigger scale. A small PCB has been developed and mounted on each drone to route packages from the Xbee module to the CAN-bus of the drone and to measure the local altitude of the drone using a ultrasonic sensor. The PCB carries an AT90CAN128 as microcontroller which build-in CAN support making it obsolete to carry an external USB CAN-controller.

(Results -*i*, discussion)

The accuracy of the vision based localisation is measured using a laser pointer pointing out the drone's 2D position on the floor making it possible to measure the variance of the drone's position. The leader-follower algorithm was also tested outside using the onboard GPS. The performance of the leader-follower algorithm is measured and discussed using plots that reveal the distance between the drones.

(Conclusion -*i*, perspective)

It is shown that it is possible to implement the leader-follower algorithm using a vision and ultrasonic based positioning system. The distance between all drones when flying indoor was +/- 10 cm which is less than the maximum accepted error. It was possible to add 5 follower-drones without editing the code showing it is a generic system. The system can further be used to indoor testing of navigation algorithms and explore the many possibilities drones has to offer. If drones at some point needs to fly indoor to help eg. Mobile robots navigating, vision might be a way to obtain an absolute indoor position for the drones.

Resumé

abstract på dansk

Reading Guide

This thesis contains three parts.

Chapter 1 gives background information about the purpose of this project. It starts giving an overview of the topic and ends up focusing on why it makes sense to make the project and what other universities have done. It further contains related work, problem statement, defined hypothesis and assumptions and limitations. A image of the final extension board can be seen to make it clear to the reader how the developed extension board and AutoQuad Ladybird drone looks

Chapter 2 describes materials and methods used in this thesis. It explains how and why the following design chooses where made concerning firmware as well as developed PCB. Each chapter starts with an introduction and ends with test results evaluating weather the choices made works or not.

Chapter 3,4,5 concerns showing, analyzing and discussing results. Evaluation of the design choices made throughout chapter 2 with respect to the hypothesis is summarized in the conclusion.

On figure 1 the different parts used in this thesis are highlighted.

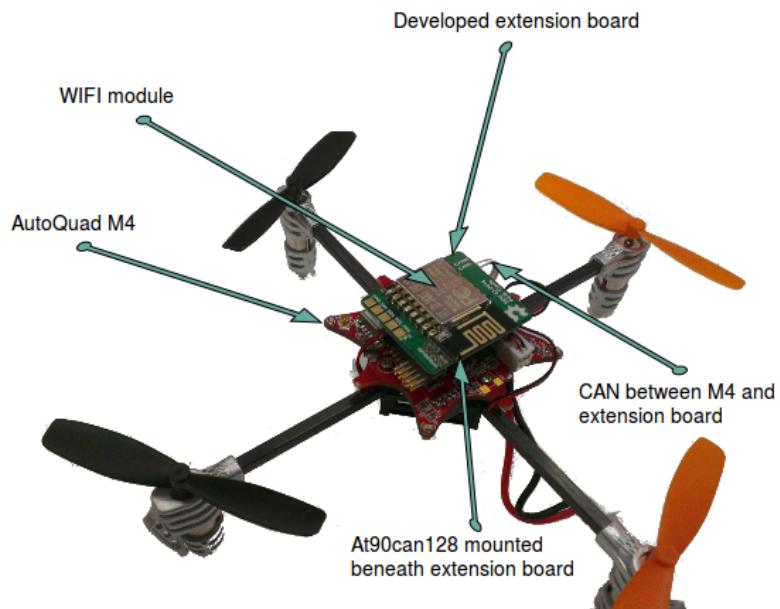


Figure 1 *Ladybird M4 drone with developed extension board*

List of Abbreviations

AQ AutoQuad Flight Pilot

Preface

Throughout the project period my classmates has been at great help to discuss and generate ideas.

Thanks to the people listed below.

- My supervisor Kjeld Jensen for providing solutions and help when needed.
- Developer of MarkerLocator Henrik Midtiby for helping me understand and adding functionality to his software.
- Carsten Albertsen for designing and soldering the extension-board.
- Friend Morten Albeck Nielsen for meeting once a week to help generating ideas, debugging, sparring and proof reading the thesis.
- Friends Mads Tilgaard Jensen, Eskild Andresen & Michael René Andersen for listening to technical issues, evaluating solutions and carrying out tests.
- My girlfriend Anna Riisberg Soerensen for proofreading the thesis and understanding the time required throughout this project period.

Table of Contents

Abstract	iii
Resumé	iv
Reading Guide	v
List of Abbreviations	vi
Preface	vii
1 Introduction	1
1.0.1 Problem Statement	5
1.0.2 Related Work	5
1.0.3 Hypothesis	6
1.0.4 Aim of project	6
2 Materials and methods	8
2.1 System architecture	9
2.2 AutoQuad extension board	10
Wireless communication module	10
Microcontroller	12
Block Schematic	12
Pins	12
Debug/ISP	13
Test of WIFI range	13
2.3 AutoQuad extension board firmware	15
2.3.1 Scheduler	15
2.3.2 Queues	19
2.3.3 Wireless communication	21
2.4 AutoQuad M4 firmware	22
2.5 Indoor localization	25
3 Results	29
4 Discussion	30
5 Conclusion	31
Appendices	35

CHAPTER 1

Introduction

This chapter will give the reader background information about UAVs and point out a problem SDU is currently facing in two ongoing projects. Further more it will describe the focus of this project and how others have managed to solve it.

Mathias: Introduction: Indøres navigation <http://innovationsfonden.dk/da/case/droner-rykker-indendoers-med-dansk-teknologi-0>

Background

UAS is an emerging technology used in lots of different areas¹.

Especially quadroters also referred to as multirotors have started to gain a lot of attention. This is, among other reasons, because it has become cheaper to produce the hardware needed to build a quadroters. Microcontrollers have become powerful enough in order to make it possible to implement control and navigation algorithms on a quadroters.²

A multiroter works by having three or more rotors mounted with equal distance from the centrum of the multiroter. Not all rotors of the multiroter spins the same way in order to compensate for the torque generated by the multiroter. A multiroter is usually equipped with a flight controller, battery, three or more electronic speed controllers and rotors. The multirotor balances using its flight controller that controls the velocity and thereby the thrust of each rotor. Usually a rotor is brushless which means it has three phases that needs to be turned on and off, so called commutation, at the right time. The job of the Electric Speed Controller is to do the commutation depending on the speed sent from the flight controller.

One of the challenge concerning multirotors is the amount of energy they are capable of carrying. If the drone is equipped with a heavy camera or other kind of payload, then the flight time begins to decrease. By looking at the nature, one can see how small animals like ants and birds manage to cooperate and thereby build or move bigger things that they would not be able to do on their own. This way of small independent, decentralized units working together is called a swarm³.

By making multirotors smaller, they get more efficient, their flight time increase and they get cheaper but of the cost of their ability to lift⁴. Therefore an idea would be to make small

¹Suraj G Gupta, Mangesh M Ghonge, and PM Jawandhiya. “Review of unmanned aircraft system (UAS)”. in: *technology* 2.4 (2013).

²Andrew Gibiansky. *Quadcopter Dynamics, Simulation, and Control*. 2010.

³https://en.wikipedia.org/wiki/Swarm_intelligence

⁴Vijay Kumar. *Robots that fly ... and cooperate*. 2016. URL: https://www.ted.com/talks/vijay_kumar_robots_that_fly_and_cooperate (visited on 05/18/2016).

multirotors cooperate to solve more heavy and complex tasks.

Multirotors can be used in a wide range of applications. If the multirotor is equipped with a camera it can quickly provide an overview of a fence, wiring, lamps etc. Multirotors are usually used in applications outside which among other reasons, might be caused by the requirement of GPS signal being available. Most multicopters are capable of flying indoor however they often have little knowledge about where they are since they lack GPS indoor. It limits the applications multirotors can be used for indoor. A research project named UAWORLD has just started which will focus on doing indoor flying.⁵. They will focus on making multirotors robust and safe enough in order to let multirotors fly indoor. They are going to develop the system in cooperation with GamesOnTrack.com which delivers the indoor 3D localization system. GamesOnTrack's localization system uses beacons and triangulation to localize objects.⁶ The are sure that drones will be used indoor at hotels, hospitals, schools and offices.

The GPS available outdoor has an accuracy of 3.5 meter ⁷ which might be adequate depending on the applications. In most flight controllers, the GPS is fused with onboard sensors like accelerometer and gyroscope however the positioning is still not adequate if the multirotor is supposed to fly close to an object within centimeters.

Even though GPS is usually available outdoor there might be places where no GPS signal is available eg. In forests or cities with high buildings. In indoor as well as outdoor applications where absolute positioning is required but GPS is not available alternative solutions such as radio triangulation, vision or totalstations could be used. However most of the multirotors available on the market only supports using their build-in GPS which might be a limitation if GPS is not available but accurate flying is necessary.

At the time of writing, SDU is collaborating with HCA airport to find anomalies in fences. *Airports are burdened by a number of required inspection tasks to maintain a high level of safety and security. Some of these tasks may advantageously be performed by a drone rather than the current manual labour, and this will save significant resources. In this project they are targeting a specific need for frequent inspection of the fence surrounding the airport shown in figure 1.1a. The inspection concerns fence holes or similar anomalies. We hypothesize that a drone is capable of unsupervised autonomous inspecting the airport fence detecting small holes down to a radius of 5 cm.*⁸

⁵<http://innovationsfonden.dk/da/case/droner-rykker-indendoers-med-dansk-teknologi-0>

⁶More information is not available online

⁷<http://www.gps.gov/systems/gps/performance/accuracy/>

⁸Application sent to Energi Fyns Udviklingsfond which has been granted, Ansøgning 2015-01-30 Energi Fyns Udviklingsfond-1.pdf on USB



(a) Part of the fence surrounding HCA Airport.



(b) Drone spreading ladybirds and gall midges to avoid spreading pesticides in organic crops

In order to avoid flying into the fence and to fly accurate enough for the camera to film, it is required to have an vertical accuracy of 2-3 cm⁹

In another project, SDU is working together with Ecobotix ApS, Aarhus University and EWH BioProduction ApS, to avoid the need of pesticides in organic crops. Pesticides are used to kill pests from the crops. When using pesticides a health risks exists for those who eat the crops. The use of pesticides also reduce the amount of diversity in nature since it is also killing beneficial organisms and potentially harm other animals in the food chain like birds. If nothing is used the crops might die, and that is very expensive to the farmer. The project has been granted 8.356.126 kr. from GUDP¹⁰

They intend to use multirotors to spread bugs like ladybirds and gall midges, over the crops to eat pests as shown in figure 1.1b.

It is required the drones fly approximately 1 meter above ground at 1.5 meter/sec. It is therefore necessary to use an RTK-GPS in order to avoid hitting the ground in case of bumps in the fields.¹¹

Many different flight controllers exists on the market. SDU UAS has decided to use AutoQuad since, among other reasons, the code is Open Source¹² and the multirotors show reliable and steady flying. An AutoQuad multirotor delivered by ViaCopter¹³ usually comes with the AutoQuad flight controller M4, Electronic Speed Controllers(ESC32) and rotors. One of ViaCopters smallest drones is delivered without Electronic Speed Controllers since H-bridges used to control the velocity of the motors are built into the M4 flight controller. ViaCopter can deliver drones in different sizes but their flight controller is the same. This means that code developed for ViaCopters Ladybird can be deployed on a large drone and it will continue to work¹⁴. However AutoQuad does not support any other source of absolute positioning other than using its onboard GPS.

Because of the research-projects at SDU, there is a need for being able

⁹Henrik Egemose Schmidt - Drone inspection of fences

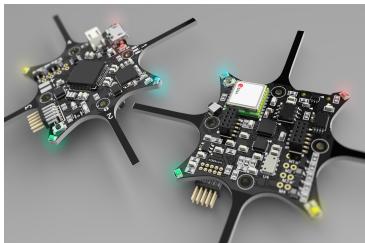
¹⁰<http://naturerhverv.dk/tvaergaaende/gudp/gudp-projekter/2015/oekodrone-skal-sprede-mariehoens-i-stedet-for-pesticider/>
last visited 18-04-2016

¹¹Jensen, K.; Larsen, R.; Laursen M.S.; Neerup, M.M.; Skriver, M. and Jørgensen, R.N. Towards UAV contour flight over agricultural fields using RTK-GNSS and a Digital Height Model. Accepted for oral presentation at CIGR-AgEng June 2016.

¹²Quatos, which is their control algorithm is not Open Source.

¹³<https://viacopter.eu/>

¹⁴Assumed the developer did not break important lowlevel tasks



(a) *M4 flight pilot*



(b) *Ladybird with mounted M4*



(c) *Eduquad with M4 + ESC32*

Figure 1.2 Pictures of AutoQuad hardware

1.0.1 Problem Statement

The current AutoQuad version does not support any other source of global positioning than the onboard GPS and thereby does not support accurate flying better than GPS and if GPS is not available, there is no alternatives supported. For AutoQuad to be used in applications requiring high accuracy or where GPS is unavailable this functionality is needed.

1.0.2 Related Work

In order to find relevant research about drones flying indoor, a few search phrases was conducted. The following keywords were used to create different phases: Indoor, environment, swarm, localization, AutoQuad, quadrotor, mini UAV, test facilities, ETH, accurate, RTK, totalstation. Based on the keywords a few papers was deemed relevant to the project and has been combined in order to give the reader an overview within the field of this project.

Developers of AutoQuad did previously try to implement RTKLib¹⁵ in AQ. Unfortunately they did manage to make it work as expected¹⁶.

One of the big players within the field of indoor navigation and controlling multiple drones accurately is the university ETHzürich and their Institute for Dynamic Systems and Modelling¹⁷. They have developed a test flying area they call "Flying Machine area" which provides facilities for doing prototype testing of new control algorithms¹⁸. The FMAs dimensions is 10*10*10m and provides nets to protect people and mattresses to protect the drone if a crash. The FMA has further been developed into a mobile installation to be used in demonstrations in Europe and North America. One of their demonstrations where used in a TED video about multirotors and their capabilities¹⁹. The multirotor usually used in the FMA is Ascending Technologies' Hummingbird with custom wireless communication and electronics.

They have build it as a module design in order to be easy to replace parts of their system by simulations and to make it scalable. One of their modules is a copilot that implements an accident handler in case of user-code crashing or sending invalid commands to the drones. They are using UDP multicast packets as communication between ground computation and flying objects. The use of UDP multicast packets between modules since to makes the system more simple but also to avoid the need of buffers to handle unsuccessful transmissions and retransmissions.

In order to detect the quadroters they are using a commercial motion capture system. Three reflective markers is mounted on each flying object in order to obtain attitude and position. They are using three cameras to reduce the risk of false positive even though two cameras would be enough to get a flying objects 6D position.

Hyun-gyu Kang, Byoung-kyun Kim, and Wangheon Lee. "Indoor localization of DRON using vision based sensor fusion". In: *Control, Automation and Systems (ICCAS), 2015 15th International Conference on*. IEEE. 2015, pp. 932–934 proposes a more simplistic approaches to do indoor navigation. They use bluetooth 4 to communicate between their multirotor(Rolling

¹⁵<http://www.rtklib.com>

¹⁶Jussi Hermansen, owner of <http://ViaCopter.eu>

¹⁷<http://www.idsc.ethz.ch/research-dandrea/research-projects/aerial-construction.html>

¹⁸Sergei Lupashin et al. "A platform for aerial robotics research and demonstration: The Flying Machine Arena". In: *Mechatronics* 24.1 (2014), pp. 41–54.

¹⁹https://www.ted.com/talks/raffaello_d_andrea_the_astounding_athletic_power_of_quadcopters

Spider) and an android phone which controls the multirotor. They have mounted a camera on the ceiling to detect the target and the flying multirotor. By doing background subtraction they can detect where the drone is in the frame by subtracting the background from each frame²⁰. By doing a convolution sum, the targets can be located. By analyzing the pixels around the location of the multirotor, they can get the heading.

Jose Luis Sanchez-Lopez et al. “A system for the design and development of vision-based multi-robot quadrotor swarms”. In: *Unmanned Aircraft Systems (ICUAS), 2014 International Conference on*. IEEE. 2014, pp. 640–648 proposes a framework to accelerate the process of prototyping multirotors behaviors. Their framework is designed for a swarm of drones to fly in a environment with obstacles. One of their design requirements is, that the framework should be highly decoupled from the application the researcher is testing in order to speed up the development process. Position estimates is obtain by using onboard IMU and optic flow. To avoid expensive motion capture systems they have used markers that can easily be recognized by cameras mounted on the drones to get a absolute 3D estimate. Each obstacle got a ArUco-marker²¹ that can be detected by the front camera mounted on the multirotor. They have decided to use ROS as middleware to provide generic interfaces between the modules used in their framework. Different multirotors can be used as long they use the same interface. Communication between multirotors and ground station(if used) is done using WIFI.

The most common type of indoor localization is using vision where the camera is either mounted in the environment or where the drone is equipped with cameras to obtain position estimates.

Timothy Stirling et al. “Indoor navigation with a swarm of flying robots”. In: *Robotics and Automation (ICRA), 2012 IEEE International Conference on*. IEEE. 2012, pp. 4641–4647 uses a different approach where they use a *Robot Sensor Network* to map the environment. The idea is that each drone can either be a beacon or explorer. Each drone alternates between these two states. Beacons stays still below the ceiling without moving while explorer flies around to unknown locations. Beacons emit IR light in order to triangulate beacons position. Beacons detecting unexplored locations calls for explorer that will become beacons and so forth until the environment is mapped. To synchronize the beacons 2.4 ghz WIFI is used. When the environment is mapped, graph searching algorithms can be used to find a path through the environment.

1.0.3 Hypothesis

If each drone’s 2D position is obtained using indoor localization and sent into each drone using CAN at the same frequency as an onboard GPS, then it is possible for at least 3 drones to follow a leader drone with a preprogrammed flight path and keep a distance of 50 cm within plus minus 10 cm to the leader and its neighbours.

1.0.4 Aim of project

The aim of this project is to test the hypothesis by making an indoor flying environment to make 3 multirotors follow a leader multirotor. Since a need from SDU has arisen of sending

²⁰Wikipedia. *Background subtraction* — Wikipedia, The Free Encyclopedia. <http://en.wikipedia.org/w/index.php?title=Background%20subtraction&oldid=697931050>. [Online; accessed 17-May-2016]. 2016.

²¹S. Garrido-Jurado et al. “Automatic generation and detection of highly reliable fiducial markers under occlusion”. In: *Pattern Recognition* 47.6 (2014), pp. 2280 –2292. ISSN: 0031-3203. DOI: <http://dx.doi.org/10.1016/j.patcog.2014.01.005>. URL: <http://www.sciencedirect.com/science/article/pii/S0031320314000235>.

RTK GPS coordinates into AutoQuad, this will also be used to test and to contribute to a scientific paper.

CHAPTER 2

Materials and methods

This chapter concerns the most important parts about how this project has been implemented. It has been split into several sections.

2.1 System architecture

Over all design:

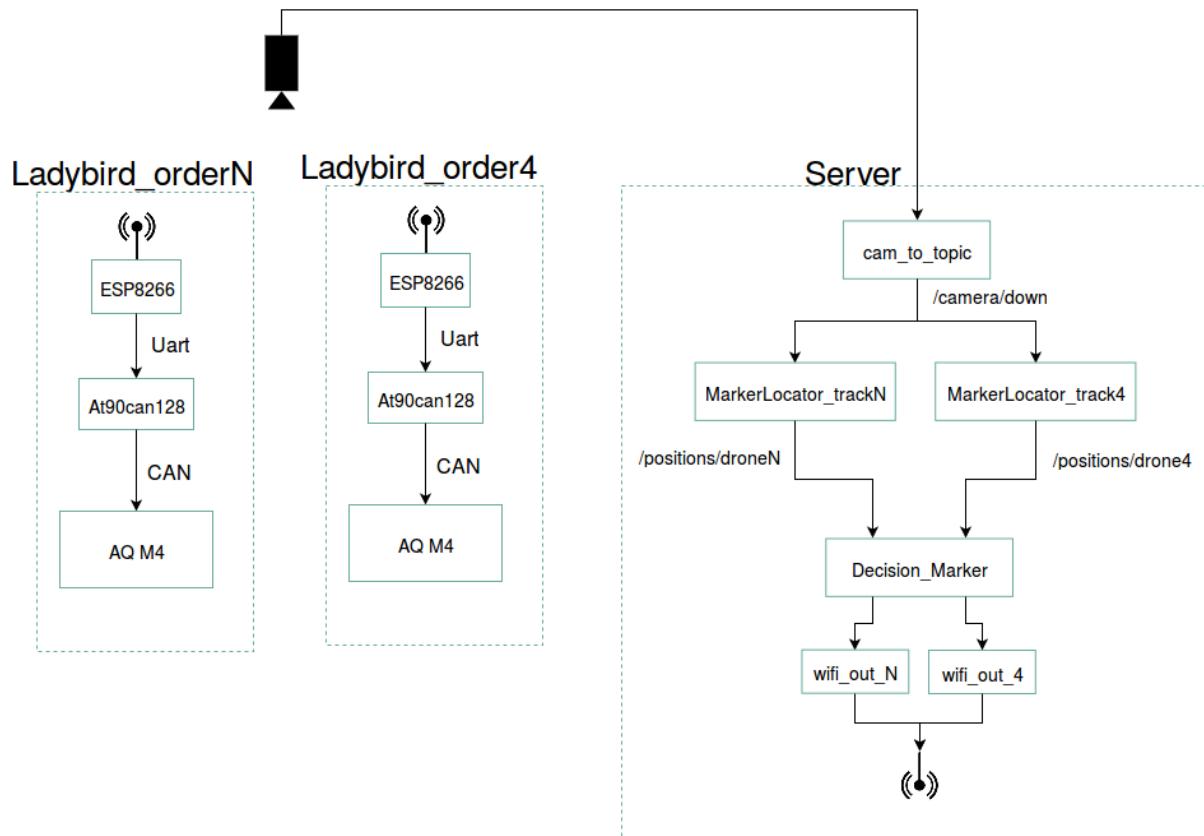


Figure 2.1 Diagram shows information flow when using indoor flying. Server detects the drones position, sends it through the ROS nodes and transmits the GPS positions using WIFI to the drones. Each drone receives its position and sends it using CAN into M4 flight controller

2.2 AutoQuad extension board

This section will go in depth with the extension-board created as an addon to the AQ M4 board. The extension-board was developed to act as a bridge between the PC and the CAN-bus using wireless communication.

Wireless communication module

An important part of the hardware is the wireless communication used between the PC and the drones. The wireless communication module has several requirements it needs to fulfill in order to make the whole system work as expected. A comparison table has been made in table 2.1 to find the wireless communication module that is best suited for the task.

The following wireless modules were considered and compared.

- **ESP8266**

ESP8266 is a general purpose 32 bit SOC with integrated WIFI 802.11 b/g/n support and buildin TCP/IP stack. It can be setup its own access point or it can connect to an existing wireless network. It runs at 80MHz and can be flashed with a custom firmware. The SOC is sold as modules with different pinouts and features such as extra flash memory ¹ and different antennas. The chip has been on the market for about two years and costs approximately 7\$. It has been widely used in DIY-projects due to its low price and because it requires a minimum of network knowledge to get up and running.² When the SOC is shipped, it comes with a preloaded firmware which either accepts AT commands or LUA scripting depending on the version of the module. These simple programming interfaces makes it quick and easy to interface the cheap.

This leads to a large community where most of the problems have been found and solved already. Arduino has been ported to ESP8266 which makes it even easier to get it up and running. Their official Arduino GitHub has 2125 commits on their master branch at the time of writing³

- **EMW3165**

EMW3165 is a SOC much like the ESP8266 supporting 802.11 b/g/n WIFI with buildin TCP/IP stack. As with ESP8266 it supports setting up an access point as well as connecting to an existing network. It has a Cortex-M4 μC which runs at 100MHz. It supports custom firmware and can be as well be bought as different modules with different pinouts and antennas. It differentiates itself from the ESP8266 by its higher frequency its 5 volts compatible pins ⁴ which makes it easier to connect other hardware which run 5 volt without the need of a logic level shifter. It has been on the market for only one year and costs approximately 9\$. Since it is a newer board than ESP8266 it has not been used in the same number of applications and thereby has a smaller community behind⁵. Their most active GitHub has 147 commits on their master branch at the time of writing⁶.

- **nRF51822**

¹<https://www.olimex.com/Products/IoT/MOD-WIFI-ESP8266/open-source-hardware>

²<http://www.esp8266.com/> - 43.000 posts in forum

³<https://github.com/esp8266/Arduino>

⁴<https://hackaday.com.files.wordpress.com/2015/07/emw3165.pdf>

⁵<http://www.emw3165.com/> - 200 posts in forum

⁶<https://github.com/SmartArduino/WiFiMCU>

nRF51822 is also a SOC, but it is using Bluetooth instead of WIFI. The nRF51822 μ C is implementing BLE which is a power efficient way of sending and receiving data. The chip supports broadcasting which could be used in this project. The μ C can be bought as a standalone component or mounted on modules as the two other μ Cs. Different modules offers different types of antenna connectors or buildin antenna on the PCB. It has not been possible to find an Arduino ported firmware that supports this μ C. To write a firmware for the μ C it has to be done using Nordic Semiconductor's proprietary SDK.

- XBee

XBee is a module that implements the Zbee standard. The Xbee modules work as a wireless serial connection. The Xbee modules supports mesh networking which means the modules by themself figure out which module is closest and makes the connection. This idea makes sense in this application since there will be multiple drones and one computer. If one drone gets too far from the PC, it can just connect to one of the other drones closer to the PC.

The Xbee solution is ready to use and requires a minimum of programming to get up and running. The modules also support GPIO for digital in and output and analog input.

Mathias: Wireless communication module: 'footmotemark til at referere til samme fod-note flere gange

Product	Size	Weight	Price	Documentation	Range	Score	
ESP8266	24x16mm ⁷	{7}	1.5g ⁸ {8}	7.5\$ ⁹ {9}	Great community {9}	?	33
EMW3165	32x16mm ¹⁰	{6}	5g ¹¹ {2}	9\$ ¹² {8}	Less available {3}	?	19
nRF51822	18x10mm ¹³	{8}	3g ¹⁴ {4}	7.5\$ ¹⁵ {9}	Ok documented {2}	30 M ¹⁶ {9}	32
XBee	24.38x27.61mm ¹⁷	{3}	3g ¹⁸ {4}	25\$ ¹⁹ {4}	Lots of DIY {9}	91 M ²⁰ {9}	29

Table 2.1 Comparisontable used to compare different wireless communication modules

The products compared in 2.1 are chosen to have approximately same specs such as onboard antenna and no need for extra components. The ESP8266 module based on the highest score but must of all because it is use in a wide range of applications and has a lot of activity on their official Arduino github. The weight of the module was measured after the decision was made. If it was heavier than the other modules it would still have been used due to the large number

⁷https://www.mikrocontroller.net/attachment/243558/fcc_11.pdf last visited 26 Maj

⁸Measured by author on chemistry weight

⁹<http://www.seeedstudio.com/depot/ESP8266-based-WiFi-module-SPI-supported-p-2486.html> last visited 26 Maj

¹⁰<https://hackaday.com/files.wordpress.com/2015/07/emw3165.pdf> last visited 26 Maj

¹¹<http://www.seeedstudio.com/depot/EMW3165-CortexM4-based-WiFi-SoC-Module-p-2488.html> last visited 26 Maj

¹²<http://www.seeedstudio.com/depot/EMW3165-CortexM4-based-WiFi-SoC-Module-p-2488.html>

¹³<http://www.fanstel.com/Product/bluenor.html> last visited 26 Maj

¹⁴<http://www.seeedstudio.com/depot/MDBT40P%C2%A0%C2%A0nRF51822%C2%A0based%C2%A0BLE%C2%A0module-p-2503.html> last visited 26 Maj

¹⁵http://www.seeedstudio.com/item_detail.html?p_id=2503 last visited 26 Maj

¹⁶https://dl.dropboxusercontent.com/u/54939426/Fanstel_BT600.pdf last visited 26 Maj

¹⁷<http://www.digi.com/products/xbee-rf-solutions/modules/xbee-802-15-4#specifications>

¹⁸<http://www.digi.com/products/xbee-rf-solutions/modules/xbee-802-15-4#specifications> last visited 26 Maj

¹⁹<https://www.sparkfun.com/products/11215> last visited 26 Maj

²⁰https://www.sparkfun.com/pages/xbee_guide

of projects using this module. In case help was needed to make the module work, plenty of projects is available online and they have an active forum²¹

Microcontroller

The first requirement for the micro-controller mounted on the extension-board was that it has a build-in CAN-controller in order to communicate with the AQ M4 board. The second requirement was that it has more than one UART to communicate with the ESP8266 and with a PC for debugging. The AT90CAN128 was chosen since the author and SDU had experience programming and using that micro-controller. Since the AT90CAN128 was already available in the authors supervisors FroboMindcontroller²², the author could start developing the firmware while the PCB for the ladybirds were made.

Block Schematic

The block schematic shown in figure 2.2 was created by the author. It was then given to Carsten Albertsen who created the schematic and did rest of the creation of the PCB. Some time was spent debugging since there was an error in the ISP pins. Later on the author had to make a correction to the board since a pin(GPIO15) on the ESP8266 that had to be grounded in order to select booting from the flash.

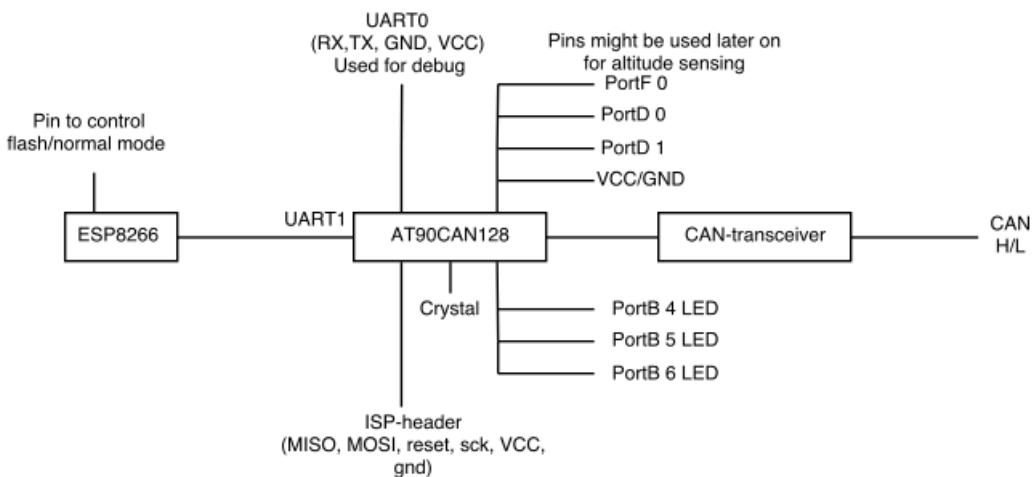


Figure 2.2 Block schematic of the extension-board developed to AQ M4. It can be seen that the ESP8266 chip is connected to the At90CAN128 using UART1 and that the AtMega is connect to a can-transceiver which communicates with the AQ M4 board.

Pins

A few pins where made available through solder pads for easy access if needed later on.

The following pins where available as solder pads:

- PortF 0 - Alternative function as ADC, channel 0

²¹<http://www.esp8266.com/> last visited 26 Maj

²²http://www.frobomind.org/index.php/FMCtrl:FroboMind_Controller

- PortD 0 - Alternative function as interrupt, INT0
- PortD 1 - Alternative function as interrupt, INT1

In case the onboard barometer isn't accurate enough, an alternative distance could be used to measure the drone's altitude with respect to the ground. PortF0 has been made available since some distance sensors give output as an analogue value. An example of such sensor is an Infrared proximity sensor.²³

As an alternative type of distance sensor, a ultrasonic could be used such as HCSR04. As output it gives a binary output with high-time proportional with the distance.²⁴. To detect the high-time, one of PortD1/0 would be useful.

Which type of sensor suits best as a distance sensor to provide altitude information to the drone is out of the scope of this report. The PCB has just been made ready to different types of sensors.

Debug/ISP

In the final schematic UART0 and ISP pins were combined in one pinheader for easy access through one cable.

Mathias: Debug/ISP: Refer to image of board

To program the AtMega the ISP pins were required to be easily accessible. UART0 was made accessible to be used as debug and programming of the ESP8266 board. The plan was to setup the AtMega as UART passthrough from UART0 to UART1. Due to a mistake²⁵ in the final schematic, both UART0 and UART1 were made accessible through the ISP/debug header. This ended up making it easier to program the ESP8266-board without using the AtMega as UART passthrough.

ESP noteS: - GPIO15 = bootmode, low for ... - GPIO0 = flash mode

<https://zoetrope.io/tech-blog/esp8266-bootloader-modes-and-gpio-state-startup>

Test of WIFI range

A test of the wifi was conducted in order to test the range of the ESP8266 module. Test of the AtMega is done in section ??

To make the test, the firmware of the ESP8266 module had to be flashed to specify which access point it should connect to. How the networking was set up can be seen in section ??.

The first test was conducted by pinging the module from the author's laptop 200 times, 10 Hz with a packet size of the data frame used in the application.²⁶ The purpose of the test was to see how the latency behaves when the distance is increased and when it stops receiving or transmitting packets.

Figure ?? shows the results.

Mathias: Test of WIFI range: Billed af pingtest

²³http://www.sharpsma.com/webfm_send/1208

²⁴<http://www.micropik.com/PDF/HCSR04.pdf>

²⁵The wrong pair of MISO/MOSI pins were made available in the ISP-header. The correct pair of MISO/MOSI is also RXD0/TXD0 as alternative function

²⁶See more about the size and content in section ??

Another test was done where the authors laptops sends datapackages to the ESP8266 module. The tests shows for how long a distance the module can be from the laptop and still receive valid packets. CRC-16 was used to validate the content of the packets. ²⁷

Mathias: Test of WIFI range: figur af antal af valid crc pakker vs. distance

A final test was made to see how the modules behave when two modules are receiving the packets. At 10 hz datapackets was sent to two modules at a distance of 10 meters.

Mathias: Test of WIFI range: Figure shows test from above

Both modules received their packets without CRC error.

It can be concluded that the chosen wifi modules, ESP8266 works well. At a distance of 100 meters it drops.... and that .. and it indicates that the communication works when more than one ESP8266 is connected to the laptop using WIFI.

²⁷See more about this in section ??

2.3 AutoQuad extension board firmware

In this chapter the development of the firmwares running on the extension board is described. Different types of schedulers for the At90CAN128 is discussed and a scheduler is chosen and developed with the required functionality. The communication between PC and M4 is further described. At the end of each section a test is conducted in order to show if the code works as expected

2.3.1 Scheduler

This chapter concerns only the Atmega. The ESP module will be described in section ??
In order to have a timing on the At90CAN128 a scheduler was chosen and implemented. The list below shows 3 different types of scheduler that was considered.

- Real-time Operating System(RTOS) provides strict timing but at the cost of overhead. A RTOS runs task in a "parallel" environment. Each task runs in a loop and the RTOS scheduler will do context switching when needed. Using a RTOS requires mutexes and semaphores to protect shared resources which increases the complexity and amount of overhead
- Super-Loop provides no timing at all, but processes data as fast as possible. It does not do any context switching and does not require mutexes or semaphores and thereby takes no overhead.
- Run-To-Complete(RTCS) scheduler is a mix of the two other schedulers. It works by waiting for a tick generated by a hardware timer and then starts executing all tasks from the beginning. The order of the task matters if there is dependency between the tasks but also to make sure the task requiring the most precise timing is at the beginning of the list of the tasks. All tasks have to be finished executing before the next tick is given in order to avoid timing being ruined.

The RTCS was chosen since it provides timing without the overhead created when doing context-switching and the need of mutex and semaphores. It further reduces the code-complexity.

Mathias: Scheduler: A little description about the scheduler implementation. Add tasks, and run the scheduler. Show how it waits for tick and the runs through all of the tasks that is in RUN state.

It was decided to implement the code in tasks to make a low coupling between the functionalities. This makes it easier to maintain and expand later if needed. The task diagram shown in figure 2.3 shows the tasks and how they do intertask communication.

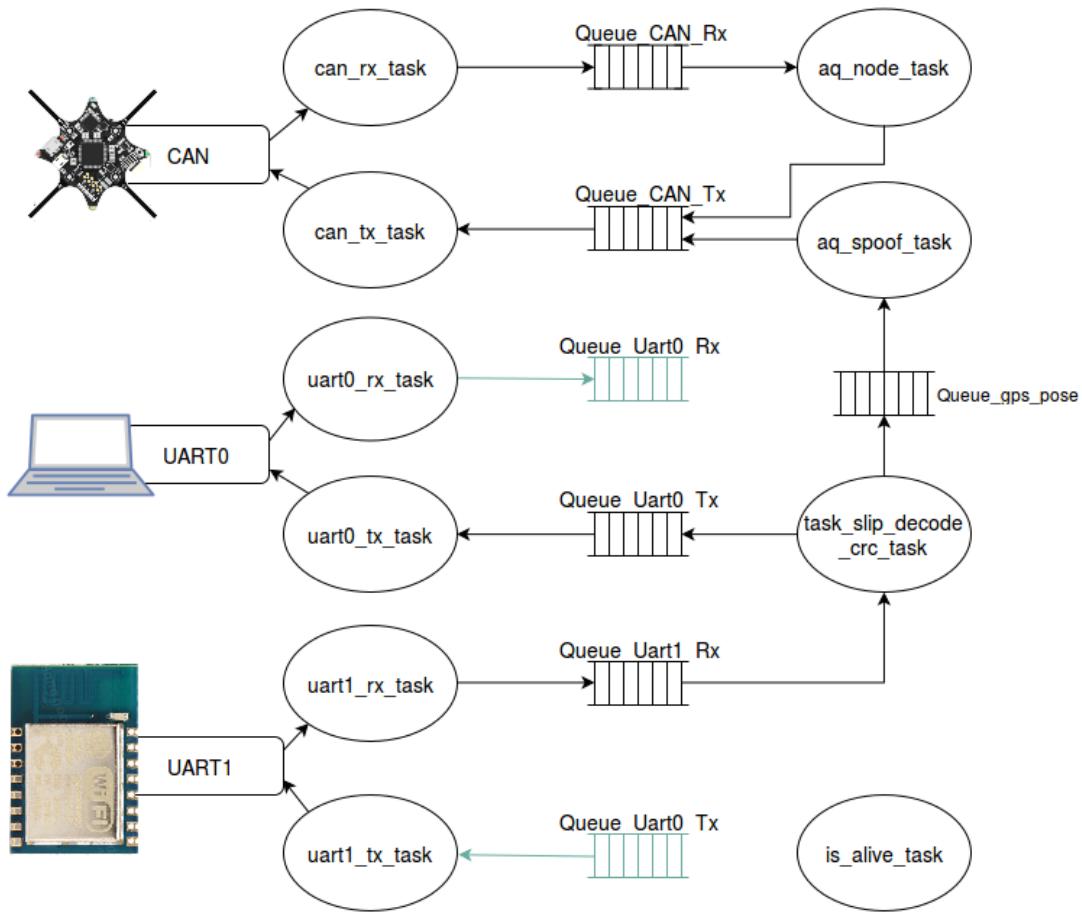


Figure 2.3 Tasks diagram showing overview of the running tasks on the At90Can128

A small description of each of the tasks is given below:

- **is_alive_task** Toggles the green led to make sure the scheduler is running. In case of stack overflow, memory leak or any other error, the Atmega will freeze and it will easily be detectable since the green led stops blinking
- **uart0_tx_task** Responsible of sending characters in the uart0_tx queue.
- **uart0_rx_task** Responsible of checking if any characters in the uart-receive buffer is available. If any, put them into the uart0_rx queue
- **uart1_tx_task** Responsible as uart0_tx_task
- **uart1_rx_task** Responsible as uart0_rx_task
- **can_rx_task** Responsible of checking if a CAN-message is available in the MOB. If any put them into the CAN_rx_queue
- **can_tx_task** Responsible of transmitting messages available in the CAN_tx_queue
- **aq_node_task** Responsible of registering the node when AQ boots.
- **task_slip_decode_crc_task** Responsible of removing SLIP characters and run CRC
- **aq_spoof_task** Responsible of converting and transmitting received GPS messages from uart1.

Mathias: Scheduler: Add description of slip and crc task, maybe also spoof and node, not sure..

Test of RTCS timing

In order to test the timing of the scheduler, a led_task was written. The task can be seen in code 2.1

Listing 2.1 RTCS task used in timing test

```

1 void is_alive_task(uint8_t my_state){
2
3     // Write to UART0
4     UDRO = my_state+'0';
5
6     switch(my_state){
7         case 0:
8             INT_LED_ON_GREEN;
9             INT_LED_OFF_RED;
10            INT_LED_OFF_BLUE;
11            set_state( 1 );
12            break;
13        case 1:
14            INT_LED_OFF_GREEN;
15            INT_LED_ON_RED;
16            INT_LED_OFF_BLUE;
17            set_state( 2 );
18            break;
19        case 2:
20            INT_LED_OFF_GREEN;
21            INT_LED_OFF_RED;
22            INT_LED_ON_BLUE;
23
24            // Set next state
25            set_state( 0 );
26            break;
27    }
28    // Wait one second
29    wait( 1000 );
30 }
```

The test was done by writing the current state of the task to UART0. A python script were made that measures the time between each character received. The script can be seen in code 2.2.

Listing 2.2 Python code used to measure time between received byte

```

1 #!/usr/bin/python
2 import serial
3 import time
4
5 ser = serial.Serial( port='/dev/ttyUSBO', baudrate=57600 )
6
7 t = time.time()
```

```
8 while True:
9     char = ser.read(1):
10    print time.time() - t, ","
11    t = time.time()
12
13 ser.close()
```

The output of the script were redirected to a file. After receiving 700 bytes the standard deviation and mean was calculated using matlab. The mean is 1.0089 sec with a standard deviation of 0.0042 sec.

Part of the variance is caused by the inaccuracy of the timing on the PC running the python code. If a more accurate measure was needed, a scope could be attached to the μ C's GPIO. Each time the scheduler enters the task the GPIO should be set high, and when it exists the GPIO should be set low. The scopes at SDU is capable of telling the variance of the off signal. It can be concluded that the scheduler performs well.

2.3.2 Queues

Test of CAN, queues

In order to test CAN and queues, a task was written. The purpose of the task was to receive a CAN-message if any available from the queue and send the ID and data from the CAN message to a PC using UART. The task used can be seen in code 2.3.

Listing 2.3 Task used to test CAN

```

1  CAN_frame frame;
2  if(QueueReceive(&Queue_CAN_Rx, &frame)) {
3      char ch;
4      /* ID out uart0 */
5      for(int i = 3; i >=0; i--){
6          ch = ((frame.id >> i*8) & 0x000000FF);
7          QueueSend(&Queue_Uart0_Tx,&ch);
8      }
9      /* ID end*/
10
11     /* MSG out uart0 */
12     for(int i = (frame.dlc-1); i >=0; i--){
13         ch = ((frame.msg >> i*8) & 0x00000000000000FF);
14         QueueSend(&Queue_Uart0_Tx,&ch);
15     }
16     /* MSG end */
17
18     /* End of line */
19     ch = '\r';
20     QueueSend(&Queue_Uart0_Tx,&ch);
21     ch = '\n';
22     QueueSend(&Queue_Uart0_Tx,&ch);
23 }
```

The command used to send CAN-messages can be seen in code 2.4.

Listing 2.4 Task used to test CAN

```
1 while true; do sleep 1; print $(date); cansend can0 1DEADB#FEDCBA9876543210; done
```

The command sends a CAN-message using a connected PEAK-CAN adapter. It sends a message each second and prints out the date to make it clear when it is sending a message.

1deadbe is the 29 bit ID and *fedcba9876543210* is the 64 bit data.

The command used to show the received HEX values can be seen in code 2.5

Listing 2.5 Command used to get UART messages

```
1 cat /dev/ttyUSB0 | xxd -c 14
```

Cat reads from /dev/ttyUSB0 and pipes its output to xxd where it is shown in HEX. -c is number of columns which is 14 due to 4 ID bytes, 8 data bytes and 2 as newline.

The result can be seen in figure ??.

00020de: 1dea dbef fedc ba98 7654 3210 0d0a	vT2...	Wed May 11 11:09:37 CEST 2016
00020ec: 1dea dbef fedc ba98 7654 3210 0d0a	vT2...	Wed May 11 11:09:38 CEST 2016
00020fa: 1dea dbef fedc ba98 7654 3210 0d0a	vT2...	Wed May 11 11:09:39 CEST 2016
0002108: 1dea dbef fedc ba98 7654 3210 0d0a	vT2...	Wed May 11 11:09:40 CEST 2016
0002116: 1dea dbef fedc ba98 7654 3210 0d0a	vT2...	Wed May 11 11:09:41 CEST 2016
0002124: 1dea dbef fedc ba98 7654 3210 0d0a	vT2...	Wed May 11 11:09:42 CEST 2016
0002132: 1dea dbef fedc ba98 7654 3210 0d0a	vT2...	Wed May 11 11:09:43 CEST 2016
0002140: 1dea dbef fedc ba98 7654 3210 0d0a	vT2...	Wed May 11 11:09:44 CEST 2016
000214e: 1dea dbef fedc ba98 7654 3210 0d0a	vT2...	Wed May 11 11:09:45 CEST 2016
000215c: 1dea dbef fedc ba98 7654 3210 0d0a	vT2...	Wed May 11 11:09:46 CEST 2016
000216a: 1dea dbef fedc ba98 7654 3210 0d0a	vT2...	Wed May 11 11:09:47 CEST 2016

Figure 2.4 Left shows output from command 2.5 and right shows command 2.4

It can be seen that the received ID and data is *1deadbef* and *fedcba9876543210* respectively. *0d0a* is \r and \n respectively.

2.3.3 Wireless communication

Communication flow

Content	Lat	Lon	Height	DOP	CRC-16
Datatype	double	double	float	float	uint16_t
Bytes	31:24	23:16	15:8	7:4	3:0

Mathias: : Ændre 0:3 til 0:1 da en uint16_t kun tager 2 bytes og ikke 4

Table 2.2 Message sent from PC to ESP8266

2.4 AutoQuad M4 firmware

AutoQuad is the flight controller used in this project. The author was among the first students using AutoQuad on SDU, but the first student to make changes to the firmware and to communicate with AQ using CAN-bus. The AutoQuad firmware was not documented at all, so much time was spent reading through code and trying to figure out how it works. A great amount of time was also spent on more practical things like getting to know their Development Environment (CrossWorks for ARM)²⁸ in order to compile their firmware, waiting for Quatos²⁹ license and getting familiar with the flashing process of AutoQuad.

Much of the gained knowledge about AutoQuad and how to do debugging has been written down to share with other students. It can be found on the USB-key handed in *Appendix/SDU-UASAutoQuaddocumentation.pdf* and *SDU-UASAutoQuadsourcedocedocumentation.pdf*. Text marked with green is written by the author.

Since AutoQuad only supports proving GPS coordinates through a serial port³⁰ another way had to be found and implemented. Sending GPS coordinates through the serial port would require the onboard GPS to be unmounted which seems like a bad solution. The CAN bus was chosen since it is already implemented in AutoQuad. However AutoQuad supports sensor inputs through CAN, GPS was not supported and there by had to be implemented.

In order to send GPS coordinates to AQ a way in had to be found. A solution would be to unmount the onboard GPS, however that removes the functionality of the M4 board to fly normally without external hardware eg. a RPI. Since AutoQuad gets its coordinates from the onboard ublox M8Q³¹ using ublox's ubx protocol, everything sent by eg. a RPI had to be encoded as ubx. Instead of making hardware changes to the M4 it was decided to use the already supported CAN-bus interface. The M4 board already uses the CAN-bus to send velocities to each of the ESC's on an EduQuad drone. AutoQuad default supports sending some sensor values using the CAN-bus, however GPS coordinates, DOPs and accuracies was not implemented. The only implementation was to receive the battery voltage and current usage and log it to an MicroSD-card. AutoQuads CAN protocol is described, implemented and tested in section ??.

When all CAN-nodes has successfully registered, different node-initializing functions run. First a summary run which sends the number and types of the nodes to QGroundStation.³². It can thus be validated by the pilot that all the ESC's and CAN-sensors are detected. After the summary, a CAN-sensor initialization happens. The initialization of each CAN-sensor happens which is to send CAN_CMD_TELEM_* described in section ?? but more important also to create a callback. The callback will then be attached to the CAN-type which in this case is CAN-sensor³³ so when AutoQuad receives a sensor reading the callback will be invoked.

Default the callback fills in the sensorvalue in an array so the sensor value can be used in another task. The canID³⁴ is then used as index so the task needing the sensorvalue knows where to look since it knows which sensorsvalue it needs. Code 2.6 shows the callback³⁵

²⁸<http://www.rowley.co.uk/arm/>

²⁹The controller, Quatos, used in AutoQuad is not Open Source so a license had to be bought by SDU

³⁰Seen by inspection of the schematic to the M4-board done by the supervisor

³¹<http://autoquad.org/wiki/wiki/m4-microcontroller/m4-gps-antenna-options/>

³²Graphical userinterface which provides general information about the drone such as battery, attitude but also waypoint functionalities

³³CAN-types are described in section ??

³⁴Described in section ??

³⁵<https://github.com/bn999/autoquad/blob/master/onboard/canSensors.c>

Listing 2.6 Callback invoked when a CAN-sensorvalue is received. It stores the value in an array indexed by canId

```

1 void canSensorsReceiveTelem(uint8_t canId, uint8_t doc, void *data) {
2     canSensorsData.values[canId] = *(float *)data;
3
4     /* Reception time of the message stored as well */
5 }
```

The callback is fairly simple and does not save the doc³⁶ which is needed in order to tell which value the CAN-GPS sensor is sending.

All of the CAN-GPS packet handling has been implemented in the callback function. A prettier solution might have been to create a task and use a semaphore to signal when there is a new GPS-packet available. Due to lack of time implementing everything was done in the callback.

Code 2.7 shows a pseudo code of how the GPS-packets is handled. In section ?? the CAN-GPS packets can be seen.

Listing 2.7 Modified callback invoked when a sensor-value is received. Shows how doc is used to tell which GPSpacket is received and when height is received the flags are set

```

1 canSensorsReceiveTelem(canId, doc, *data) {
2     if doc == CAN_DOC_LAT then
3         canData.latitude = data
4
5     if doc == CAN_DOC_LON then
6         canData.longitude = data
7
8     if doc == CAN_DOC_DOP then
9         canData.xDOP = data[x]
10    ..
11    if doc == CAN_DOC_ACC then
12        canData.satellites = data[0]
13        canData.fix = data[1]
14        canData.xAcc = data[x]
15    ..
16    canData.heading = data[n-1]
17
18    if doc == CAN_DOC_VEL then
19        gpsData.velx = data[x]
20    ..
21    if doc == CAN_DOC_ALT then
22        gpsData.height = data
23        if gpsData.fix == 1 and gpsData.satellites >= 8 then
24            gpsUpdatetime = now()
25            setFlag (gpsData.gpsPosFlag)
26            setFlag (gpsData.gpsVelFlag)
27        else:
28            debug_to_QGroundStation
29 }
```

³⁶Described in section ??

The *data* pointer given as parameter to the callback is of void pointer. Some pointer gymnastics is done in order to get the right elements from the CAN-packet. If the received CAN-packet is of 8*1 bytes, the void pointer is casted to an uint8_t pointer so each byte can be retrieved by using the casted pointer as an array.

When the flags are set, the task updating the UKF will run ³⁷. Code 2.8 shows a snippet from the task updating the UKF when the position or velocity flag is set.

Listing 2.8 Snippet of run.c as psudeocode which updates the UKF when position flag or velocity flag is set

```
1 if IsFlagSet(gpsData.gpsPosFlag) == yes then
2     navUkfGpsPosUpdate(gpsData.lastPosUpdate, gpsData.lat, gpsData.lon,
3                         gpsData.height, ....);
4     ClearFlag(gpsData.gpsPosFlag);
5
6 else if IsFlagSet(gpsData.gpsVelFlag) == yes then
7     navUkfGpsVelUpdate(gpsData.lastVelUpdate, gpsData.velN, gpsData.velE, ....);
8     ClearFlag(gpsData.gpsVelFlag);
```

³⁷<https://github.com/bn999/autoquad/blob/master/onboard/run.c#L110> last visited 23 maj

```
can0 00000000 [0] can0 01C00000 [8] EF BE AD DE 03 09 00 00 can0 0E000041 [6] EF BE
AD DE 00 00 can0 14CD0042 [2] 00 08 can0 14CC0043 [2] 0A 00
```

```
seq tæller op så rate/value bliver acknowledged can0 00000000 [0] can0 01C00000 [8] EF BE
AD DE 03 09 00 00 can0 0E000041 [6] EF BE AD DE 00 00 can0 14CD0042 [2] 00 08 can0
00400002 [8] 00 00 00 00 00 00 00 00 can0 14CC0043 [2] 0A 00 can0 00400003 [8] 00 00 00 00
00 00 00 00
```

2.5 Indoor localization

In order to do indoor flying there is a need of some sort of localization since GPS is not available indoor. Vision was decided based on what mostly others are using and some further advantages. Instead of making the vision, it is decided to use an existing tracker called MarkerLocator written by Henrik Midtiby. However the MarkerLocator lacks a proper quality measure so that is implemented. A few tests were made and the MarkerLocator with implemented quality measure is working quite well

In order to do accurate flying indoor a localization system is needed. In the Related Work section, it can be seen vision with a camera mounted pointing down is used by others. Compared to use one or more cameras mounted on the drone, an advantage of using a camera mounted on the ceiling is that the camera will not be harmed if the drone crashes and that one camera can be used to detect several drones. However if the position is needed in more than 2D, more than one camera might be needed(depending on the algorithm used) but it still scales better than mounting one or more cameras on each drone.

Based on previous experience, the MarkerLocator written by Henrik Midtiby was chosen as indoor localization. Its using OpenCV³⁸ and implemented in python. It works by detecting markers as shown in figure 2.5

Mathias: Indoor localization: insert image of markerLocator marker with different orders

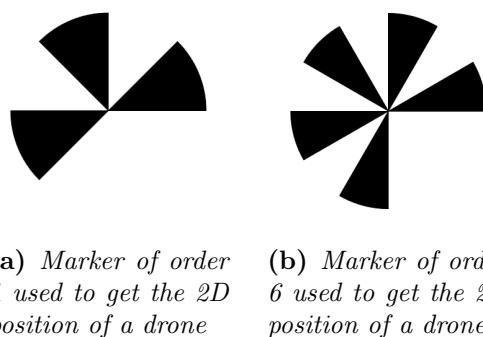


Figure 2.5 The markers have one arm less than the order of the marker for the MarkerLocator to detect the orientation of the marker

The MarkerLocator works by making a convolution sum of a complex kernel on each frame obtained from the camera. The location where it fits best is said to be the location of the marker in the frame. How it works in detail is out the scope of this project. The markers shown in figure 2.5 is of different orders. The order is equal to the number of black arms minus one since the missing arm is used to detect the orientation of the marker. Different orders can be used and thereby detect more than one marker in each frame. Unfortunately it can only get the

³⁸<http://opencv.org/>

2D position and 1D orientation of the marker. Since doing a convolution of the entire frame is relatively slow³⁹, the MarkerLocator has a mode called WindowMode. It works by searching in only a small area around the last known position of the marker and thereby speeding up the progress⁴⁰.

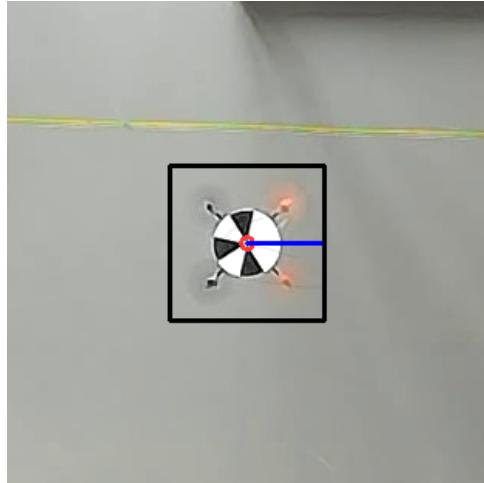


Figure 2.6 The MarkerLocator searches only for the marker around the last known position of the marker in a frame of 100*100px.

If the marker moves out of the window, the MarkerLocator is still looking in only that window. Therefore it is important to have a quality measure that can be used to decide whenever a full convolution of the frame has to be done or if the marker has been found within the window.

The MarkerLocator has a quality measure build-in used to tell how well the marker is detected. However it is not used in the MarkerLocator to tell if a full convolution has to be done. The quality measure implemented in the MarkerLocator is a hack⁴¹ and is known from previous applications that it is a bad measure of the right marker is detected.

In cooperation with Henrik Midtiby a few quality measures was developed. The overall idea was to compare the kernel used to do the convolution with the marker found in the frame. Different algorithms where used to give a normalized value telling how similar the found marker is to the kernel. Figure 2.7 shows the different solutions tried.

³⁹Processing one fullHD frame takes approximately 0.38 sec. Measured with build in timer in the MarkerLocator

⁴⁰Approximately 0.0041 sec

⁴¹Said by Henrik Midtiby

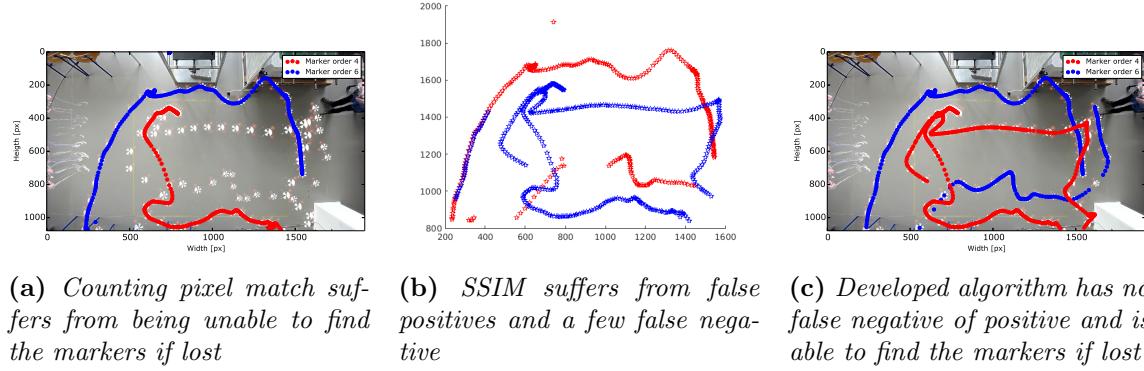


Figure 2.7 Different approaches to get a quality measure explaining how well the right marker is found.

Figure 2.7a is a native approach of comparing all pixels in the kernel with the pixels in the found marker. A counter is incremented upon each match and at the end divided by the number of pixels compared in to normalize. A threshold determines whether a marker is found and the next scan should be done in the window of if a full scan is required. The best result is obtained using a threshold of 0.4. If the threshold were lowered false positives started to occur.

Figure 2.7b uses an algorithm developed to compare similarities in images. The details of this algorithm is out of scope the details of this project. The implementation in `scipy-image`⁴² was used. It can be seen it performs better than the native approach but a lot of false positive and a few false negative exists. It also suffers from not detecting the markers compared to the native approach. A threshold of 0.3 were used. If the threshold were increased, it would detect less markers.

Figure 2.7c shows a simple algorithm the author came up with. If the MarkerLocator is looking for a marker of order 4 and it has detected a marker and its orientation, the algorithm calculates where the location of the arms. It then checks a pixel in each arm and increments a counter if the pixel is black. When it has checked all the arms it compares the counter with the order the MarkerLocator is looking for and returns if they match or not. This method does not provide a scalar as output but a binary and thereby has no threshold. However in order to detect if a pixel is black or not, a threshold has been used. The threshold was set to 100 which has shown good results doing tests and flight.

During development of quality measures it was noted that if the MarkerLocator does a full search because it cannot find a marker with order 4, it slows down the detection of the marker of order 6. This is because the MarkerLocator is implemented in one process without threading. However this has been solved by splitting up the MarkerLocator in 2 different processes so they run independently of each other. More about this in section ??

Perspective correction

In order to use centimeters as measure of the position of the markers and to correct if the camera is not pointing directly down, the build-in perspective correction in the MarkerLocator were used. It works by using homography⁴³ to make the transformation from pixels to some chosen unit which in this case is centimeters.

⁴²<http://scikit-image.org/>

⁴³Jan Erik Solem. *Computer Vision with Python*. first. O'REILLY, 2012.

By creating four markers with known distance to each other at the expected flight height⁴⁴ and find these markers in the frame, it is possible for the perspective corrector to make the transformation. Figure 2.8 shows the setup used. A picture was taken from the ceiling-camera and the four black corners of the whiteboard could be found in the frame. The distance between the black corners in centimeters and the distance in px is given as input to the perspective correcter. The locations of markers is then transformed into the plane made by the whiteboard. Depending on where the whiteboard is placed in the frame origin can be placed. The placement of the coordinate system can be seen in section ??

A test was conducted to get the accuracy of the MarkerLocator. Two markers with order 4 and 6 was placed at the expected flight-height and the distance between the two markers was calculated using Pythagoras.

This was done with distance 60 centimeters measured using a ruler. The real distance measured by a ruler was 60 cm and the MarkerLocator gave

Another test was conducted in order to see how stable the MarkerLocator is. 547 position detections was done while the marker was placed steady at the flight height. It shows a mean position in x of -8.1487 with variance of 0, y position with mean -39.5046 and variance 0.

Some of this inaccuracy is caused by measuring error and placing of the whiteboard. If higher accuracy is needed this should be done again more carefully.

It can be concluded that using the MarkerLocator with the improved order detection it is possible to detect two drones without having any false positive/negative. By making a test of the distance between two markers there is an error of 0.81 cm. The MarkerLocator seems stable with a variance of zero.



Figure 2.8 Setup used to make 4 points in the flight-height. The four corners of the whiteboard was used and then found in the image.

⁴⁴Since only 2D positioning is available, a plane where the drone is expected to fly is decided

CHAPTER 3

Results

CHAPTER 4

Discussion

CHAPTER 5

Conclusion

List of Figures

1	Ladybird M4 drone with developed extension board	v
1.2	Pictures of AutoQuad hardware	4
2.1	Diagram shows information flow when using indoor flying. Server detects the drones position, sends it through the ROS nodes and transmits the GPS positions using WIFI to the drones. Each drone receives its position and sends it using CAN into M4 flight controller	9
2.2	Block schematic of the extension-board developed to AQ M4. It can be seen that the ESP8266 chip is connected to the At90CAN128 using UART1 and that the AtMega is connect to a can-transceiver which communicates with the AQ M4 board.	12
2.3	Tasks diagram showing overview of the running tasks on the At90Can128	16
2.4	Left shows output from command 2.5 and right shows command 2.4	20
2.5	The markers have one arm less than the order of the marker for the MarkerLocator to detect the orientation of the marker	25
2.6	The MarkerLocator searches only for the marker around the last known position of the marker in a frame of 100*100px.	26
2.7	Different approaches to get a quality measure explaining how well the right marker is found.	27
2.8	Setup used to make 4 points in the flight-height. The four corners of the white-board was used and then found in the image.	28
5.1	Example of CAN arbitration where node 15 has the lowest ID and thereby highest priority	37
5.2	Registering a new node in AQ	41
5.3	Successful SENSOR registration	43
5.4	Test of python CAN test	44
5.5	Block schematic of the connected components	45
5.6	Test-setup shown	46
5.7	Comment	46
5.8	Test coordinates plotted	47
5.9	QgroundStations plot of AQ's belief in where the drone is	47
5.10	The EduQuad drone with the hardware used in the test	49
5.11	Plot of h/vDOP from logs when the drone was airborn	50
5.12	Nep-6p connected to a M4 through a RPI	51
5.13	Scaling factors used when using Neo-6p GPS	54
5.14	Path walked. If looking close it can be seen the path was walked twice, once with onboard GPS then using Neo-6p	54

List of Tables

2.1	Comparisontable used to compare different wireless communication modules	11
2.2	Message sent from PC to ESP8266	21
5.1	Table shows the identifier bits used in AutoQuad CAN messages	36
5.2	Table shows abbreviations used in table 5.1	36
5.3	Table showing the 4 types of priority in AQ	38
5.4	Descriptions of the FIDs mentioned in code 5.3	39
5.5	Packet sent from node when registering in AQ	40
5.6	CAN messages from RPI to AutoQuad containing 8 byte latitude	52
5.7	CAN messages from RPI to AutoQuad containing 8 byte longitude	52
5.8	CAN messages from RPI to AutoQuad containing velocities each of 2 bytes	52
5.9	CAN messages from RPI to AutoQuad containing 8 byte altitude	52
5.10	CAN messages from RPI to AutoQuad containing DOPs each of 1 byte	52
5.11	CAN messages from RPI to AutoQuad containing accuracies each of 1 byte and heading in 2 bytes	52
5.12	Table shows precision required	53

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Appendices

5.1 AutoQuad CAN protocol

In order to spoof the onboard GPS, the CAN-bus was chosen as input to AQ. The CAN-bus is already implemented and widely used on a ViaCopter drone to communicate between AQ and hardware like ESCs, PDB etc. Much time was spent reading through the source code and trying to figure out how the protocol works. The developers behind AQ say, that the code is the documentation and thereby have not written any real documentation.

Figuring out how it works was done using debugging utilities such as breakpoints and looking at the content of the different memory locations in CrossWorks.

More debugging tricks can be seen in appendix ???. To further investigate the protocol a PEAK-CAN adapter were connected to a Ladybird drone and several python scripts were developed to send and receive messages from AQ.

The author did not go into details about messages used between AQ \leftrightarrow ESC's and AQ \leftrightarrow OSD.

CAN Protocol description

A Peak-CAN adapter were used throughout the project. It supports High-speed ISO 11898-2¹ which is a standard that states the properties of physical layer. Its max speed is 1 mbit which is the speed AQ uses to communicate on the CAN-bus. AQ uses CAN 2.0B which has 29 identifier bits. AQ is not using an existing protocol on the application layer. The developers created their own to suit their needs.

Identifier bits

A generic look at a AQ CAN messages can be seen in table 5.1. The normal function of the identifier bits is the priority of the messages. A CAN controller can then be setup to only allow certain messages to be processed depending on their identifier bits. The identification bits has been split up in AQ to contain information about the sender, receiver etc. Which is not normally saved information in a CAN message.

CAN Message							
Identifier bits [29 bits]							Data bits [max 64 bits]
LCC [28:27]	TT [26]	FID [25:22]	DOC [21:16]	SOID [15:11]	TID [10:16]	SEID [5:0]	

Table 5.1 Table shows the identifier bits used in AutoQuad CAN messages

In figure 5.2 the abbreviations can be seen.

LCC	Logical Communications Channel
TT	Target Type
FID	Function ID
DOC	Data Object Code
SOID	Source ID
TID	Target ID
SEID	Sequence ID

Table 5.2 Table shows abbreviations used in table 5.1

¹<http://www.peak-system.com/PCAN-USB.199.0.html?&L=1>

Each of the elements in an AQ messages will be explained how they are used in AQ.

Logic Communication Channel

LCC is the priority of the message. To understand how LCC works, one needs to look into CAN arbitration. As stated in ISO-11898-2, a 0 is the dominant bit and a 1 is the recessive bit. The example in figure 5.1 shows two nodes each transmitting a packet. The arbitration only happens during the transmission of the identifier bits. In the example on bit 8, Node 16 losses the arbitration and stops transmitting. Node 15 keeps transmitting its packet because it has lower identifier bits and thereby higher priority.

	Start Bit	ID Bits												The Rest of the Frame
		10	9	8	7	6	5	4	3	2	1	0		
Node 15	0	0	0	0	0	0	0	0	1	1	1	1		
Node 16	0	0	0	0	0	0	0	1					Stopped Transmitting	
CAN Data	0	0	0	0	0	0	0	0	1	1	1	1		

Figure 5.1 Example of CAN arbitration where node 15 has the lowest ID and thereby highest priority

LLC in a message can take one of the defines in code 5.1

Listing 5.1 LLC defines

```

1 #define CAN_LCC_EXCEPTION ((uint32_t)0x0<<30)
2 #define CAN_LCC_HIGH      ((uint32_t)0x1<<30)
3 #define CAN_LCC_NORMAL    ((uint32_t)0x2<<30)
4 #define CAN_LCC_INFO      ((uint32_t)0x3<<30)

```

Table 5.3 Table showing the 4 types of priority in AQ

Name	Value	Priority (lowest first)
EXCEPTION	0000	0
HIGH	0001	1
NORMAL	0010	2
INFO	0011	3

Target Type

Target type can either be “node” or “group” depending on if the receiver(s) is one or more nodes.

Listing 5.2 Target type defined in AQ

```

1 #define CAN_TT_GROUP      ((uint32_t)0x0<<29)
2 #define CAN_TT_NODE       ((uint32_t)0x1<<29)

```

The GROUP is used when AQ sends its reset-msg upon startup.

When the authors node sends a sensor-measure to AQ it will be of type CAN_TT_NODE.

Function ID

Function ID describes the function of the CAN message. If it is a PING, ACK, NACK, etc. It simply states the function of packet so the receiver node knows what to do with the message. Different types of functions can be seen in code 5.3

Listing 5.3 Excerpts from AQ’s list of function defines

```

1 #define CAN_FID_RESET_BUS ((uint32_t)0x0<<25)
2 #define CAN_FID_ACK        ((uint32_t)0x1<<25)
3 #define CAN_FID_REQ_ADDR   ((uint32_t)0x7<<25)
4 #define CAN_FID_GRANT_ADDR ((uint32_t)0x8<<25)
5 #define CAN_FID_CMD        ((uint32_t)0x3<<25)

```

Table 5.4 describes the FIDs shown in listing 5.3.

Mathias: : Dette er forkert, eftersom alle defines er taget fra AQ’s can.h så der passer det..

If a message is if FID CAN_FID_CMD, the Data Object code will be used as the command. It should be noted from code 5.3 that the FID’s is moved 25 positions to the left but FID is shown in table 5.1 is at bits 22:25. The offset of three bits is due to the way ARM’s CAN

registers is implemented. The three initial bits in CAN_TIxR and CAN_RIxR (registers used to transmit and receive respectively)² registers are general information about the CAN messages like whether it is extended (Part B.0) or not.

Table 5.4 Descriptions of the FIDs mentioned in code 5.3

FID	Description
CAN_FID_RESET_BUS	Message sent by AQ when powered up
CAN_FID_ACK	Message sent to AQ when acknowledging a received message
CAN_FID_REQ_ADDR	Messaged used when a node on the bus tries to register itself as a node on the bus
CAN_FID_GRANT_ADDR	Messaged sent by AQ when it registers a node as a node on the bus.

Table 5.4 shows a description of the 4 FIDs used when a node is registered.

Data Object Code

Data Object code is used as a parameter to the FID. Data Object Code can have different values depending on the fid. Code 5.4 shows a function using DOC when message FID is CAN_FID_CMD.

Listing 5.4 Snippet of AQ's can.c:365

```
1 void canProcessCmd(... ,uint8_t doc, ...) {
2     switch (doc) {
3         case CAN_CMD_STREAM:
4             ...
5             break;
6         case CAN_CMD_TELEM_VALUE:
7             ...
8             break;
9         case CAN_CMD_TELEM_RATE:
10            ...
11            break;
12    }
13 }
```

In section 5.1 DOC is used by the author to tell which part of the GPS data is getting sent but where FID is CAN_FID_TELEM.

Mathias:: Fixe ref til section om GPS spoof

Source/Target/Network ID

When referred to source/target ID but without respect to either sender or receiver but just a CAN-node, then it is referred to as NetworkId. When a node registers itself in AQ, it gets assigned a NetworkId.

²http://www2.st.com/content/ccc/resource/technical/document/reference_manual/59/b9/ba/7f/11/af/43/d5/CD00171190.pdf/files/CD00171190.pdf/jcr:content/translations/en.CD00171190.pdf:688

Sequence ID

The sequence id is incremented on transmission of each message. It is used when eg. A CAN-node sends a reply to a get-message, it is then including the sequence id of the get-message so AQ knows what it receives a reply for.

Data bits

The data bytes does not have a general definition, it depends on the function id. With some FIDs the data field may contain additional parameters.

Eg. When FID is CAN_FID_REQ_ADDR, data has the fields shown in table 5.5

Table 5.5 *Packet sent from node when registering in AQ*

64 bits							
0	0	CanId	CanType	UUID3	UUID2	UUID1	UUID0
7	6	5	4	3	2	1	0

UUID is a unique address generated by each node on the bus. In ESC32v2³ the address is calculated using XXH-hashing algorithm. The algorithm generates a 32 bit hash from a given input value and a salt. The input to XXH in ESC32v2 is the unique ID that every ARM in the STMF32⁴ family has. Code 5.5 shows how it is implemented in AQ.

Listing 5.5 Snippet showing UUID generated in ESC32v2

```

1 can.h:20
2 #define CAN_UUID 0x1FFFF7E8
3
4 can.c:753
5 canData.uuid = XXH32((void *)CAN_UUID, 3*4, 0);

```

CanType is the type of the node trying to register. Eq. SENSOR, ESC and SERVO.

CanID is the number of the CanType node trying to register. When an ESC32v2 is trying to register it sends CanId as the ESC number ranging from 1 to the number of ESC's mounted on the drone. The CanID is assign to each ESC manually as part of the configuring.

Registering a node in AQ

When the AQ is starting up, it is transmitting a CAN_FID_RESET_BUS to the bus. When each CAN-node receives the messages, they send out a CAN_FID_REQ_ADDR message in order to get registered as a node in AQ. If a node on the bus does not get registered it will not be able to communicate with AQ.

When AQ receives an CAN_FID_REQ_ADDR, it sends back a CAN_FID_GRANT_ADDR to tell the node that the registration is successful and to assign the node its networkID. This id is used later to identify the node when it is transmitting a message or when AQ wants to send

³<https://github.com/bn999/esc32/blob/master/onboard/can.c>

⁴http://www2.st.com/content/ccc/resource/technical/document/reference_manual/59/b9/ba/7f/11/af/43/d5/CD00171190.pdf/files/CD00171190.pdf/jcr:content/translations/en.CD00171190.pdf

out a message to that specific node. The sequence diagram in figure 5.2 shows the described sequence.

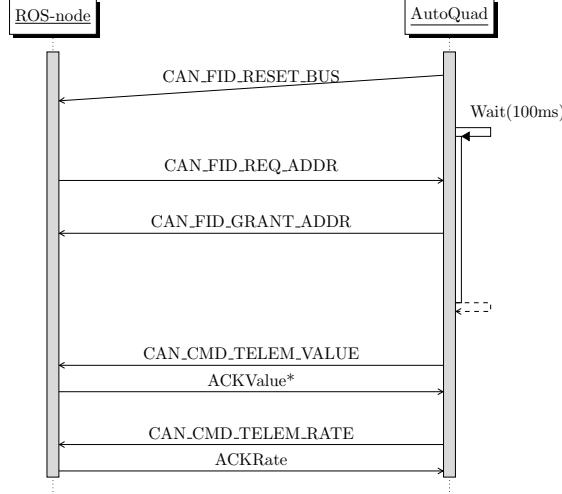


Figure 5.2 Registering a new node in AQ

Depending on the canType set in the data-field when a node is transmitting a CAN_FID_REQ_ADDR, AQ might send zero or more messages back to the node.

In figure 5.2 it can be seen that AQ sends back CAN_CMD_TELEM_VALUE and CAN_CMD_TELEM_RATE because the CanType is set to SENSOR. Each of the two messages has two fields in the data field, that contains information about the stream. CAN_CMD_TELEM_VALUE is used to request telemetry from a node that registered itself as a SENSOR. CAN_CMD_TELEM_RATE is the requested telemetry rate from AQ. Default is 10 hz ⁵.

A timeout timer is started when each message has been sent. If an ACK is not received after each message within 250 ms ⁶ a timeout counter is incremented. At the time of writing this information is not used but might be later on.

Code in 5.6 shows a snippet⁷ from AQ where AQ waits for nodes to request an address.

Listing 5.6 Snippet showing AQ waits for devices

```

1 canResetBus();
2
3 // wait 100ms for nodes to report in
4 micros = timerMicros() + 100000;
5 while (timerMicros() < micros)
6     // extend wait period if more nodes found
7     if (canCheckMessage(0))
8         micros = timerMicros() + 100000;
  
```

AQ waits default 100 ms for nodes to request an address. If canProcessMessage() returns true a node tried to register and the registration period is extended 100 ms.

⁵<https://github.com/bn999/autoquad/blob/master/onboard/canSensors.h:24>

⁶<https://github.com/bn999/autoquad/blob/master/onboard/can.h:71>

⁷<https://github.com/bn999/autoquad/blob/master/onboard/can.c:547>

Registering node test

Implementation of a CAN-node running on a PC was initially done in python. The python module *SocketCan*⁸ supports PeakCAN adapter out of the box.

Code 5.7 shows a snippet of main.py.

Listing 5.7 Snippet showing AQ registration from python

```

1 # Create autoquad handle
2 autoquadNode = AutoQuadNode('can1', 'socketcan')
3
4 # Wait for reset msg transmitted by AQ.
5 autoquadNode.WaitForReset(timeout=1000);
6 print "Recevied readymsg"
7
8 # Register node, CanType as sensor and CanID as PDB ampere
9 msg = autoquadNode.RegisterNode(CAN_TYPE_SENSOR, CAN_SENSORS_PDB_BATA)
10
11 # Wait for telemetryTryValue
12 msg = autoquadNode.recv()
13 # Parse message
14 msg = CanMessage(msg)
15
16 # Print all values received, __str__(self) overwrited
17 print msg
18
19 # ACK TelemValue
20 autoquadNode.AnswerRequestTelemValue(msg)
21
22 # Wait for telemetryRate
23 msg = autoquadNode.recv()
24
25 # Parse message
26 msg = CanMessage(msg)
27
28 # ACK TelemRate
29 autoquadNode.AnswerRequestTelemRate(msg)

```

When a node has successfully registered, it is shown in QgroundStation as shown in figure 5.3. It can be seen 4 motors were connected to the CAN bus, but also that the spoofed sensor was registered.

⁸http://python-can.readthedocs.io/en/latest/socketcan_native.html

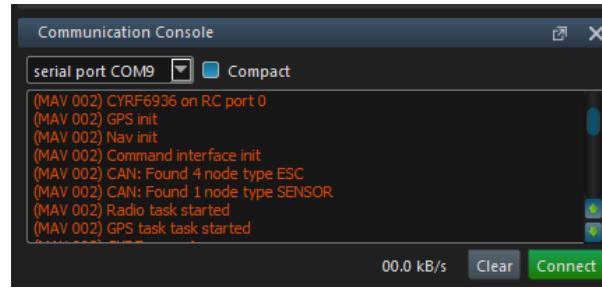


Figure 5.3 Successful SENSOR registration

Spoofed current test

When an AQ PDB is mounted on a drone, the PDB measures voltage, current and temperature and sends the measurements to AQ where they get logged.

The code in section 5.1 was further developed into a sensor simulator that spoofs current measurements into AQ to test the registering works probably.

A logger extension-board was mounted on the M4-board in order to save the measurements to a MicroSD-card.

Code 5.8 shows the implementation where a sinus is generated to simulate a current and how it is transmitted to AQ.⁹

Listing 5.8 Snippet spoofing current measurements into AQ

```
1 def RegistrerTelem(self):
2     # self.sinus is a list of sinus values
3     sensor_value = self.sinus[self.phase]
4
5     # Get next value next time and do overrun
6     self.phase+=1
7     self.phase = self.phase % 20
8
9     # Pack as IEEE754 float
10    sensor_value_float = pack('>f', sensor_value)
11
12    # Create list of float-bytes as integers
13    data_float = [int(ord(elm)) for elm in sensor_value_float]
14
15    # Reverse list and append empty data
16    data_float.reverse()
17
18    # Send to AQ. id = CAN_FID_TELEM (02c00000) | Sourceid 1 (00000800) |
19    #           CAN_SENSORS_PDB_BATA (00004000)
20    self.send(0x02c04800, data_float)
```

The method defined in code 5.8 was run every 100ms.

After the code ran for a few seconds the SD card was plugged into a PC and QgroundStation configured to make a plot of the PDB_CURRENT-field. The plot can be seen in figure 5.4

⁹someguy2993.

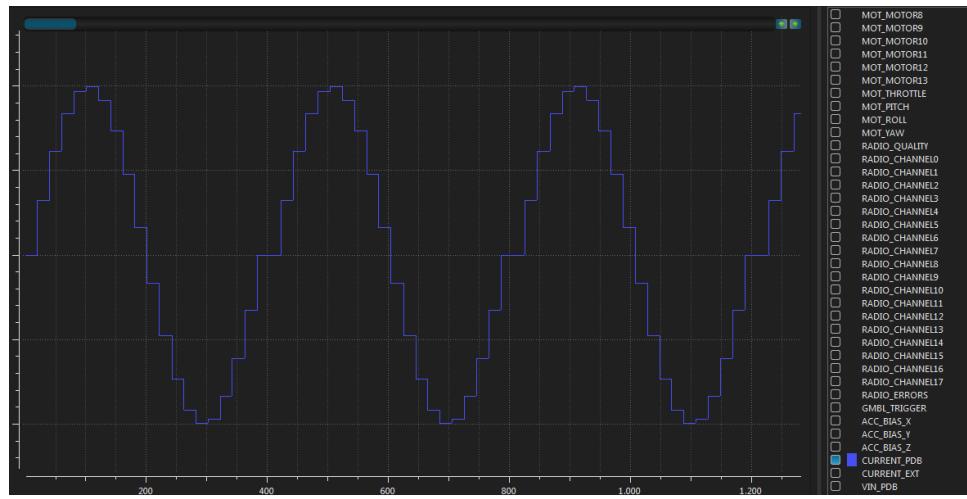


Figure 5.4 Test of python CAN test

Figure 5.4 shows the sinus generated from the node as expected.

5.2 Test of spoofed GNSS

Testing of the spoofed GNS was split intro two subtests.

The first test was conducted in order to validate the GPS spoofing using the CAN-bus works when the drone is laying on a table.

Test 1 can be seen in 5.2.1.

The second test was conducted as the first test, but when the drone is airborn.

Test 2 can be seen in 5.2.3

Figure Y shows the waypoint list uploaded to the drone. It is expected that the drone will behave as if it was using its onboard GPS. The GPS positions will be gathered in a rosbag to be used later on in test2. A flight with the onboard GPS will be done in order to have a reference flight.

Testx Test two will be conducted much the same way as test1. However the GPS will be replaced with a lightweight RTK GPS. The RTK GPS positions will also be saved in a rosbag for later analyse. Is is expected that when using the RTK GPS the drone is closer to its waypoints shown in figure Y, than when using a normal GPS.

5.2.1 Test of spoofed positions indoore

Introduction The purpose of this test was to see if the GPS coordinates was spoofed correctly and read probably by AQ and to validate the ROS node responsible for creating CAN messages was working as long as the drone is laying on a table. If this works, it shows that the UKF works with the spoofed coordinates as expected, and that the author of the report can spoof the GPS position from a vision based localization system.

A rosbag was used to collect data from the GPS since it publishes data to a topic when played as a node did when the recording took place. This results in no code has to be written and when the code works with a rosbag it also works when it is replaced with a node providing real-world data.

Test

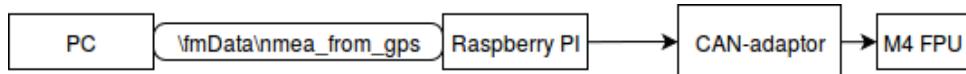


Figure 5.5 Block schematic of the connected components

Figure5.5 shows the connected componenets.

To get the NMEA strings from the GPS, an already existing Frobomind component will be used. It reads from a serial port, and publishes the parsed NMEA string to /fmData/nmea_from_gps. Rosbag was then used to save the messages. The code written by the author will then subscribe to /fmData/nmea_from_gps and publish the CAN-messages to another topic. A third node which is also a part of Frobomind will then subscribe and send the CAN-messages.

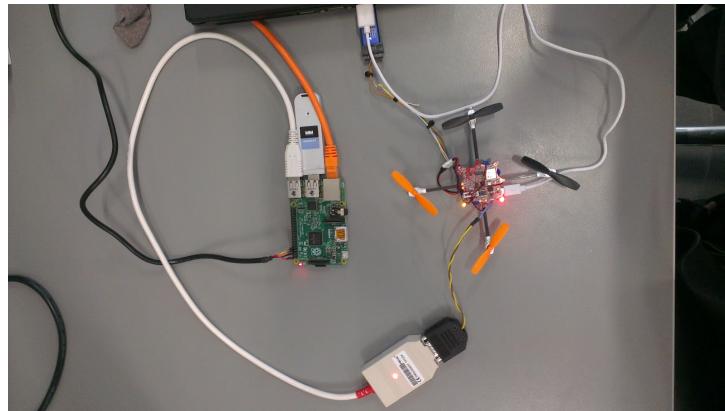


Figure 5.6 Test-setup shown

The RPi is connected directly to the PC using the orange ethernet cable. The rosbag was stored and played on the PC, so the ethernet cable were used to share rostopics between the PI and the PC. The roscore where running on the PC.

The Ladybird drone is connected to the RPI using a PEAK CAN-adapter to transfer CAN messages. The Ladybird is powered by the white USB-cable and to show the position of the drone in QgroundStation. The PC is connected to the drone using ST-Link SWD to easier start, stop and restart the drones firmware during the test. To access a TTY on the PI, an FTDI cable has been connected to the PC.

In order to obtain GPS-testdata to spoof into AQ, a rosbag was used to record data collected by the GPS mounted on the authors laptop. The setup can be seen in figure 5.7

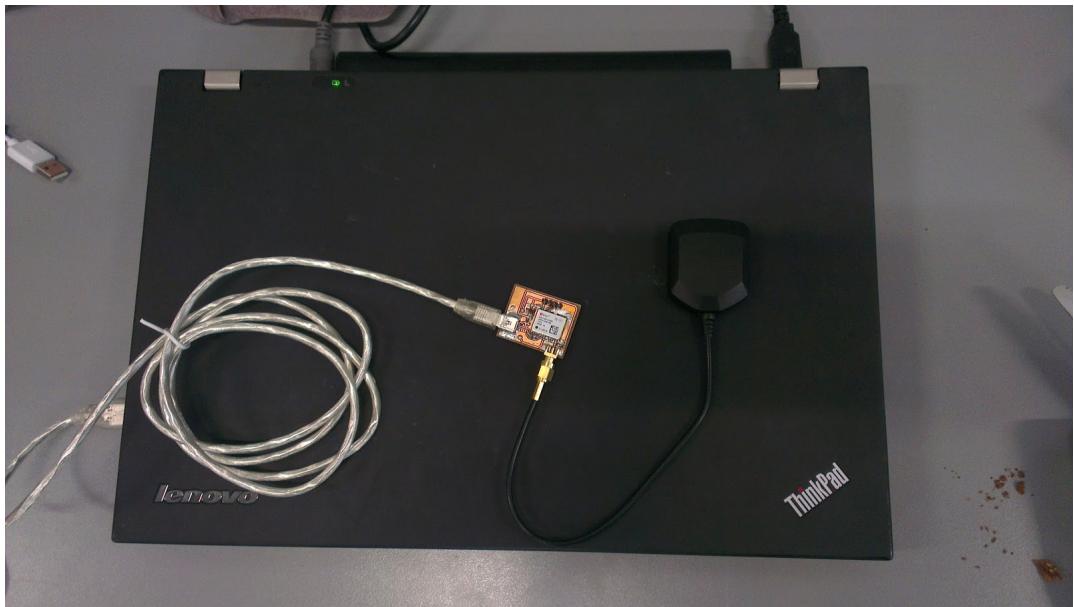


Figure 5.7 The Neo6-P GPS (PCB developed by SDU), u-blox active GPS antenna ¹⁰ and authers laptop used in this test

The coordinates recorded by the rosbag is shown in figure 5.8. FreeNMEA¹¹ was used to plot the GPGGA messages obtained from the GPS.

¹¹<http://freenmea.net/>

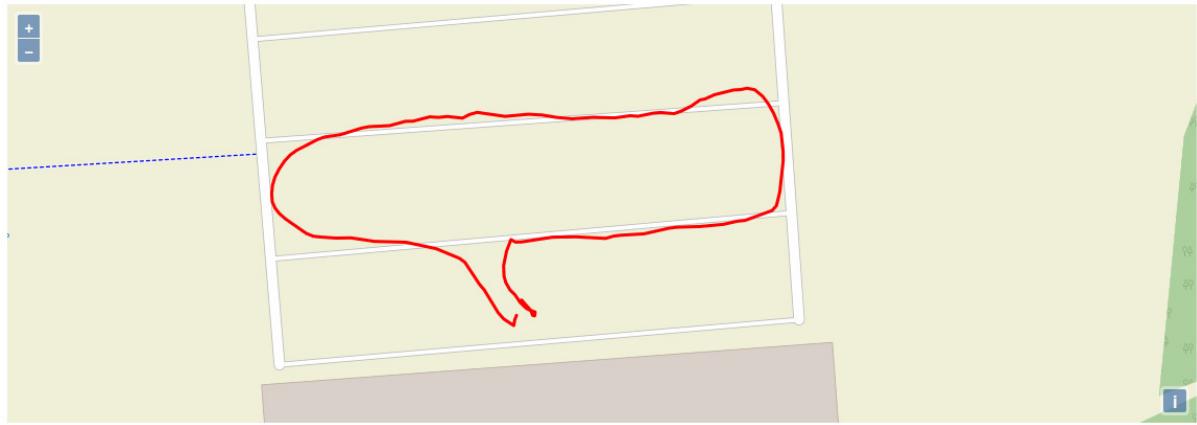


Figure 5.8 Test coordinates plotted

The rosbag containing the GPS coordinates where played on the Rpi, to see if the ROS node responsible for converting GPGGA messages into CAN messages were working. QgroundStation plots AQ's belief in where the drone is. The plot can be seen in figure 5.9

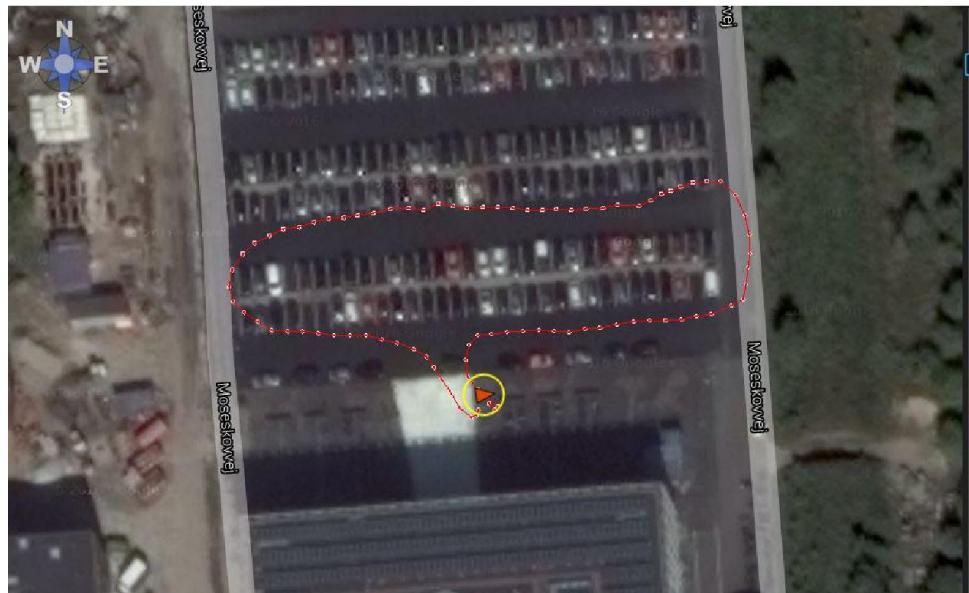


Figure 5.9 QgroundStations plot of AQ's belief in where the drone is

Conclusion This test visually confirms that the coordinates is spoofed correctly and read probably by AQ as long as the drone is laying on a table. Passing this test means there is reason to believe that it also works when the drone is airborne.

5.2.2 Initial test flight with spoofed GPS

Introduction The purpose of this test was to see if the GPS spoofing worked when the drone was airborn. The same hardware and software were used as in section 5.2.1, though with a few changes.

The GPS used in test 1 to collect coordinates were mounted on the EduQuad.

The idea was to pass-through the GPS coordinates from the Neo 6-P GPS to AQ. If the CAN spoofing works as expected the drone should behave normally when flying in position-hold

mode.

Test

Figure 5.10 shows how the hardware were mounted on the EduQuad. It was temporary mounted with strips and tape to avoid short circuiting.

Mathias: Initial test flight with spoofed GPS: Opdater billede med test-equipment

In test 1 the altitude of the drone was hardcoded since it had no relevance in the test. Though in test 2 if was necessary since the UKF¹² uses the altitude from the GPS to estimate the position of the drone. Furthermore the following check where inserted to make sure only valid GPS coordinates were fed into the AQ:

Listing 5.9 Quality checks added to discard bad positions

```

1 // default low accuracy
2 gpsData.hAcc = 5; // Meters
3 gpsData.vAcc = 5; // Meters
4
5 if(gpsData.fix == 1){ // Single point solution
6     if(gpsData.hdop < 3){
7         if(gpsData.satellites >= 5){
8             AQ_PRINTF("Recv. Valid GPGGA\n",0);
9             // High accuracy
10            gpsData.hAcc = 2.5; // Meters
11            gpsData.vAcc = 2.5; // Meters
12            // Set flag to process new message
13            CoSetFlag(gpsData.gpsPosFromCanFlag);
14        } else {
15            AQ_PRINTF("Satellites: %f \n", gpsData.satellites);
16        }
17    } else {
18        AQ_PRINTF("HDOP: %f\n", gpsData.hdop);
19    }
20 } else {
21     AQ_PRINTF("Fix: %f\n", gpsData.fix);
22 }
```

¹²<https://github.com/bn999/autoquad/blob/master/onboard/run.c#L111>

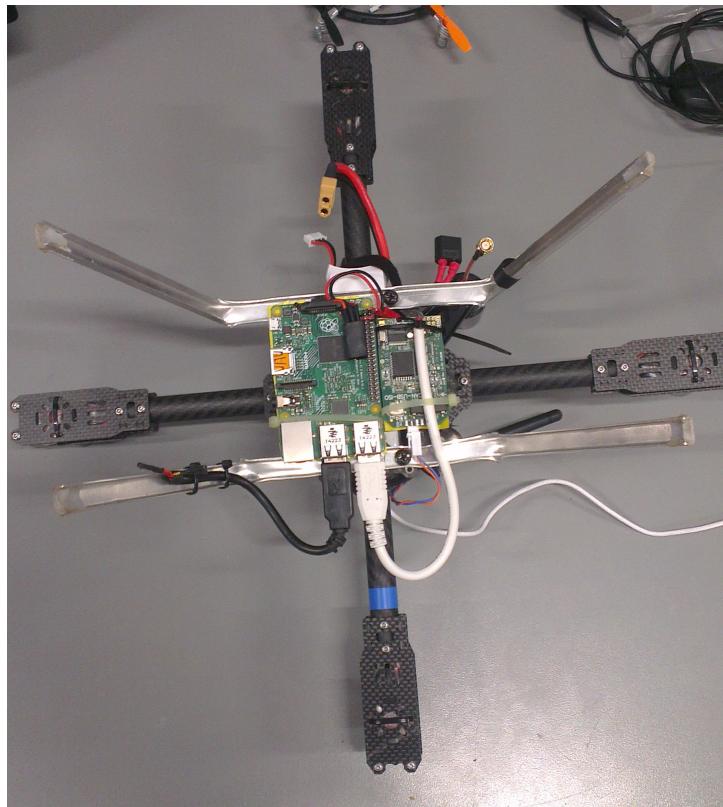


Figure 5.10 The EduQuad drone with the hardware used in the test

An extra battery was mounted on the drone to supply the Rpi. The ROS nodes running on the Rpi had to be start up before AQ starts registering notes on the CAN-bus. If the nodes was not started up, they would not reply to AQs reset-msg it sends when it is booting.

When the ROS-node were connected to the CAN bus, it showed that the ROS-node needed extra checking on CAN messages in order to detect difference between messages targeted the ROS-node and messages targeted the ESC32-nodes.

A bug in the *can_socketcan* -node used to communicate with the Peak-Can adapter where found a fixed. It was later on merged back into Frobomind ¹³ **Conclusion**

The test did not go as expected. The test was carried out under a time pressure since the author's supervisor only had 30 minutes to carry out the test.

The author did though gain experience when having multiple CAN devices connected to the CAN-bus.

Several things went wrong through the test:

- The onboard GPS was not disabled
- The author accidentally forgot to set the DOP values used in AQ
- No reference flight after the firmware were flashed for the first time.
- The GPS antenna was not mounted in the middle of the frame as the onboard antenna.

¹³<https://github.com/FroboLab/frobomind/pull/12>

Figure 5.14 shows the DOP value is lowering which indicates that AQ was using its onboard GPS.

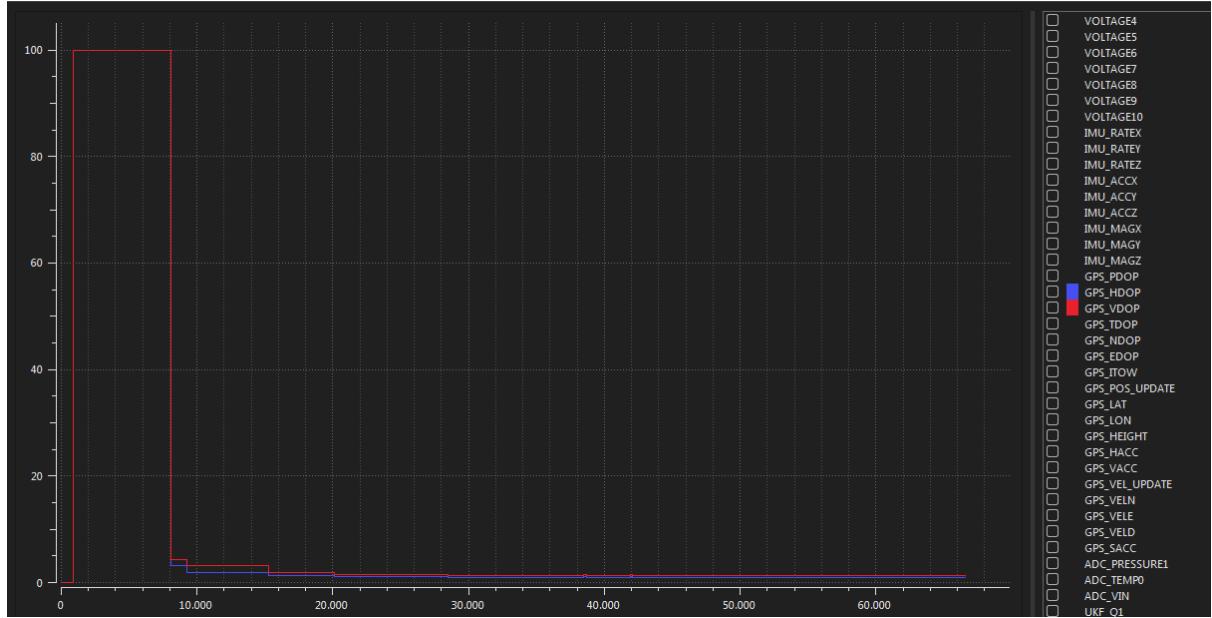


Figure 5.11 Plot of $h/vDOP$ from logs when the drone was airborne

The test will be carried out again.

5.2.3 Comparison of onboard and spoofed GPS

This test was made together with Kjeld Jensen in order to get one step further to spoofing the drone's onboard GPS with an RTK GPS. A ublox Neo6-P GPS and an active λ ANTENNE δ was mounted on a EDUQuad drone to obtain the drone's position. A RPI was used on the EDUQuad to convert GPGGA and GPRMC from the Neo6-p GPS to CAN-messages. The test was done by walking 20 meters with the EduQuad two times to compare the output of the UKF with the different GPS's. The values used to spoof the GPS was found by analyzing a logfile from a regular flight to see the range of the values such as accuracy, DOP etc. when the drone was in the air. Values available from the Neo6-p GPS, was used directly to spoof the onboard GPS and values not available was either calculated or hardcoded. Three tests were made due to a few code-errors but only the first and the last will be described. This test was also relevant for the indoor flying since the indoor application requires the position of the drone can be spoofed and the accuracies and DOPs can be set.

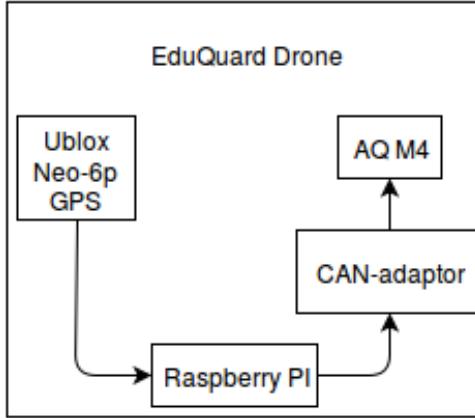


Figure 5.12 Nep-6p connected to a M4 through a RPI

In order to easily switch between the onboard GPS and the Neo-6P GPS during the test, a switch on the Spectrum DX9¹⁴ was read in AutoQuad's firmware to decide which of the two GPS's data should be used. When a GPS update(time, position or velocity) is received from the onboard GPS, the struct showed in code 5.10 is filled in.

Listing 5.10 Quality checks added to discard bad positions

```

1  typedef struct {
2      ...
3      double lat;
4      double lon;
5      float height; // above mean sea level (m)
6      float hAcc; // horizontal accuracy est (m)
7      float vAcc; // vertical accuracy est (m)
8      float velN; // north velocity (m/s)
9      float velE; // east velocity (m/s)
10     float velD; // down velocity (m/s)
11     float speed; // ground speed (m/s)
12     float heading; // deg
13     float sAcc; // speed accuracy est (m/s)
14     float cAcc; // course accuracy est (deg)
15     float pDOP; // position Dilution of Precision
16     float hDOP;
17     float vDOP;
18     float tDOP;
19     float nDOP;
20     float eDOP;
21     float gDOP;
22
23     //Used in GPS spoof
24     uint8_t fix;
25     uint8_t satellites;
26     int out_cnt;
27
28     ...
29 } gpsStruct_t;
  
```

¹⁴<http://www.spektrumrc.com/Products/Default.aspx?ProdId=SPMR9900> last visited 21. Maj

In order to spoof the onboard GPS correctly, the author and his supervisor decided to overwrite all of the relevant elements in the struct. However, the RTC was set from the onboard GPS.

Tables tables 5.6 to 5.10 show the CAN-messages created to send data to fill in the struct.

DOC	CAN_DOC_LAT
Value	Latitude
Bits	63:0

Table 5.6 CAN messages from RPI to AutoQuad containing 8 byte latitude

DOC	CAN_DOC_VEL			
Value	VelN	VelE	VelD	speed
Bits	63:48	47:32	31:16	15:0

Table 5.8 CAN messages from RPI to AutoQuad containing velocities each of 2 bytes

DOC	CAN_DOC_LON
Value	Longitude
Bits	63:0

Table 5.7 CAN messages from RPI to AutoQuad containing 8 byte longitude

DOC	CAN_DOC_ALT
Value	Altitude
Bits	63:0

Table 5.9 CAN messages from RPI to AutoQuad containing 8 byte altitude

DOC	CAN_DOC_DOP						
Value	gDOP	eDOP	nDOP	tDOP	vDOP	hDOP	pDOP
Bits	55:48	47:40	39:32	31:24	23:16	15:8	7:0

Table 5.10 CAN messages from RPI to AutoQuad containing DOPs each of 1 byte

DOC	CAN_DOC_ACC						
Value	Heading	vAcc	hAcc	cAcc	sAcc	Fix	Satellites
Bits	63:48	47:40	39:32	31:24	23:16	15:8	7:0

Table 5.11 CAN messages from RPI to AutoQuad containing accuracies each of 1 byte and heading in 2 bytes

In order to know the required bytes to send latitude and longitude with a precision of 1 cm, the author used the datum WGS84¹⁵ to estimate the worst-case error at equator.

WGS-84¹⁶ states that the semi-major-axis(a) of the earth is 6378137.0 m and that the flattening factor is 1/298.257223563. From these two values the semi-minor-axis(b) can be calculated using equation 5.2.3

$$b = a \cdot \left(1 - \frac{1}{298.257223563}\right) \quad (5.1)$$

Given the formula of the circumference of an ellipsoid:

$$\text{circumference} = 2 \cdot \pi \sqrt{\frac{1}{2}(a^2 + b^2)} \quad (5.2)$$

¹⁵WGS-84 used in AQ

¹⁶http://www.unoosa.org/pdf/icg/2012/template/WGS_84.pdf last visited 22 maj

Equation 5.2.3 gives a circumference at equator of 39873752.0 meters.

By dividing 39873752.0 by 360, one get how many meters pr. degree.

$$\frac{39873752.0}{360} = 110760 \frac{m}{deg} \quad (5.3)$$

Table 5.12 was made to see how many decimals is required to obtain different precisions.

Table 5.12 Table shows precision required

Decimal place	Decimal degrees	Distance
0	1	110760 m
1	0.1	11076.0 m
...
7	0.0000001	7.75323 cm
8	0.00000001	0.775323 cm

It can be seen that 8'th decimal is necessary to get below 1 cm. To see if a float can handle number smaller than $1 \cdot e - 8$, *eps* from MatLab was used¹⁷.

Listing 5.11 Check if float is precise enough of a double has to be used

```

1  eps(single(180.0)) = 1.5259e-05
2  eps(double(180.0)) = 2.8422e-14

```

In code 5.11 *eps* is given with 180 as input since 180 is the largest integer possible with using latitude and longitude. It can be seen that the smallest number a float can represent is $1.5259e-05$ but a precession of $1 \cdot e - 8$ is needed. However a double can easily handle that which makes the latitude and longitude of the CAN-messages 8 bytes each.

2 bytes are allocated for each velocity, speed and heading. In order to send 2 decimals, each value was multiplied by 100 when sending and divided by 100 when received by AutoQuad.

Only one decimal for rest of the values was deemed necessary and was thereby multiplied and divided by 10.

To tell the UKF in AQ how much to believe in the GPS coordinates, the onboard GPS feeds the UKF with DOP factors. The DOP factors expresses how well the satellites are placed. If they are all located around the same spot, the DOP factors will be high since the triangulation becomes less accurate. The DOP factors has no unit but is simply a scaling of the error estimate.¹⁸

Mathias: Comparison of onboard and spoofed GPS: Insert image from normal flight

¹⁷<http://se.mathworks.com/help/matlab/ref/eps.html>

¹⁸Anna B.O. Jensen Keld Dueholm Mikkel Laurentzius. *GPS*. third. Page 45-47. Nyt Teknisk Forlag, 2015.

Figure ?? shows a flight using onboard GPS where the DOP values were read. The values listed in table 5.13 was used and multiplied by the hDOP received from the Neo-6P GPS.

The pDOP was set to 1.75 times higher than the hDOP since it incorporates error from both vDOP and hDOP¹⁹. vDOP is usually 1.5-2 times higher than hDOP.²⁰

tDOP was set to 1.5 times higher than hDOP since time error causes position error.²¹

Since hDOP can be split into nDOP and eDOP, they each of some of the error factor.

Mathias: Comparison of onboard and spoofed GPS:
Gdop, skal den ikke være højere siden den har både
vDOP, hDOP og tDOP

22

Figure 5.13 Scaling factors used when using Neo-6p GPS

Dop	Value
pDOP	1.75*hdop
hDOP	1*hdop
vDOP	1.5*hdop
tDOP	1.5*hdop
nDOP	0.7*hdop
eDOP	0.7*hdop
gDOP	1*hdop

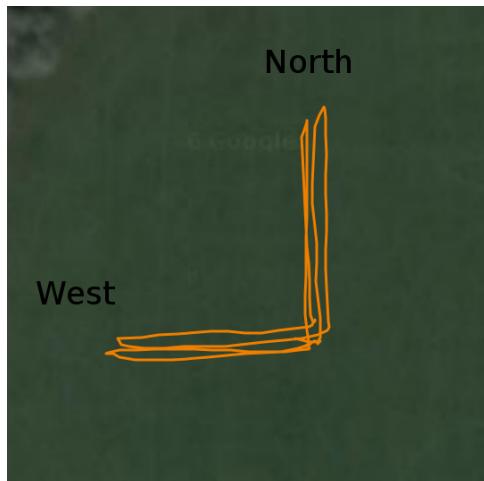


Figure 5.14 Path walked. If looking close it can be seen the path was walked twice, once with onboard GPS then using Neo-6p

The test was conducted by walking 20 meters²³ north, 20 meters south, 20 meters east and 20 meters west. After walking 20 meters a small break of five seconds was held. Figure ?? shows the walked path.

Mathias: Comparison of onboard and spoofed GPS:
Figure med gpgga plot

The coordinates plotted in figure ?? was from the first test. Figure ?? shows a plot of the position with x-axis as time.

Mathias: Comparison of onboard and spoofed GPS: Plot af northing and easting fra ukf

¹⁹Keld Dueholm, GPS.

²⁰Keld Dueholm, GPS.

²¹<http://www.environmental-studies.de/GPS/Dilution-of-precision/dilution-of-precision.html> last visited 22 maj

²²Keld Dueholm, GPS.

²³Measured by counting footsteps

Figure ?? matches with the walked path seen in figure ???. The line crossing several times is the switch on the Spectrum DX9 transmitter. It can be seen how the path repeats itself after the switch has been switched.

Mathias: Comparison of onboard and spoofed GPS: plot af pos og switch samt dop så man kan se de ændrer sig ved skift.

Figure ?? shows the same plot but where the vDOP and hDOP has been added. It can be seen when zoomed in, how the DOP values is also changing since the DOPs are higher when switching to the Neo-6p GPS.

Mathias: Comparison of onboard and spoofed GPS: Billeder der viser højden/hastigheden er mere woobly siden DOP er mega lav, den stoler for meget på GPS

Figur der viser højden samt højdehastigheden

figur der viser vele og veln der ikke virker.

Ny test, samme måde som første test, dog med følgende resultater ²⁴

²⁵

5.3 Documentation made throughout this thesis

²⁴fejlen skyldtes forkert blevet hevet ud fra C++ vector samt en variabel var brugt forkerte sted.

²⁵Keld Dueholm, *GPS*.