

Instrumental Odour Monitoring System Optimized for Drone Applications

Javier Alonso-Valdesueiro^{*†}, Santiago Marco-Colás^{*†} and Agustín Gutiérrez-Gálvez^{*†}

^{*} Department of Electronic and Biomedical Engineering, University of Barcelona,

[†] Signal and Information Processing for Sensing Systems, Institute for Bioengineering of Catalunya

Abstract—In this contribution, a novel design for an Instrumental Odour Monitoring System (IOMS) is presented. This evolution of the IOMS concept is designed to be mounted on a drone, enabling the generation of 3D maps of gas concentrations and odour levels during flight. It features fast-response gas chambers, a rapid data acquisition architecture, a modular design, and fast GPS RTK tracking. The performance of this innovative design has been tested under controlled conditions, comparing its performance with existing designs. The results show that the time for the gas concentration inside the IOMS to reach the limit of detection of the sensors is approximately 3-7 seconds faster than that observed in traditional IOMS designs. Additionally, measurements taken during test flights with a conventional IOMS are compared with those obtained using the new design. In every flight, the new IOMS produces results tenths of seconds faster than the conventional designs. These results, both in the laboratory and in the field, indicate that the modifications in the new IOMS design enable it to respond rapidly to changes caused by the drone's swift movements. This fast response and rapid tracking make the novel design more suitable for fast 3D map of gas concentrations and odour level than conventional IOMS designs.

Index Terms—IOMS; Drone-based odour monitoring; 3D odour mapping; Gas concentration mapping; Fast-response gas chambers; Electronic nose; Malodours; Machine learning; Odour intensity prediction

I. INTRODUCTION

INSTRUMENTAL Odour Monitoring Systems (IOMS) have been deployed in Wastewater Treatment Plants (WWTPs) over the past decade [1]–[4]. These systems are used for odour quantification and monitoring due to their effectiveness in measuring gases such as H_2S , NH_3 , and others producing malodorous [5], [6]. Consequently, in recent years, they have become commercial products and are being installed at WWTP fences and critical points across Europe [4], [7]–[9]. However, these deployments are time-consuming, requiring extensive and costly calibration procedures. Furthermore, they lack flexibility in case of plant changes and cannot produce a comprehensive map of the plant unless multiple IOMS units are deployed around and inside the facility [10].

In recent years, drone-based IOMS have emerged for rapid gas concentration characterization and odour mapping in the industrial landscape [11]–[13]. Their applications include

methane leak control [14], fire detection with source location [15], and air quality monitoring [16]. In particular, studies on WWTPs have shown that these systems can produce 3D maps of gas concentration results much faster than commercial IOMS for the entire plant [17], enabling data scientists to develop odour quantification models [18], [19].

Despite these results, experience has shown that drone-mounted designs struggle to follow rapid variations of its surrounding air [12], [13], [19]. Consequently, the drone's speed (typically ~ 10 m/s) when moving around the plant for 3D mapping is limited by the response time of the measuring system. Also, windy conditions produce plumes of odour and the conventional IOMSs struggle to work in these conditions (wind speed ≤ 10 km/h). This limitation reduces the applicability of IOMSs to quantify static sources and operate in favorable conditions.

Recent studies have shown that a careful design of the gas chambers containing the sensors in an IOMS significantly reduces the time needed to reach the sensors' limit of detection [20]. This reduction in response time impacts on the requirements of sensor data and GPS location data acquisition architectures of the IOMS. Consequently, the traditional IOMS design, even in its drone-mounted version [12], requires a substantial review.

This work presents the mentioned review of the conventional IOMS design, featuring a very fast response time, rapid data acquisition architecture, and centimeter-precise RTK GPS location. This platform is capable of tracking rapid changes in the surrounding air, addressing the limitations of conventional IOMSs when mounted on drones (such as drone speed and windy weather conditions). During laboratory tests, the novel design has shown faster response (in the tenths of seconds) to an odorous step than a conventional IOMS and fast plume tracking. This behavior has been confirmed during test flights (at UPC facilities droneLab, Castelldefels, Spain).

Therefore, this contribution is organized as follows: Section II provides a description of the novel IOMS, including its gas chambers, data acquisition architecture, communications, and GPS data management. Section III presents a comprehensive performance characterization of the IOMS by comparing its response in various experiments with that of a conventional design. Section IV summarizes the flying tests assessing the IOMS performance. Finally, Section V summarizes the achievements of this design, outlining the potential applications of this optimized IOMS.

This contribution has been funded from ATTRACT, a European Union Horizon 2020 research and innovation project, under grant agreement No. 101004462. The research has been also partially funded by IBEC-CERCA consortium and Generalitat de Catalunya (expedient 2021 SGR 01393).

Manuscript received April 19, 2021; revised August 16, 2021.

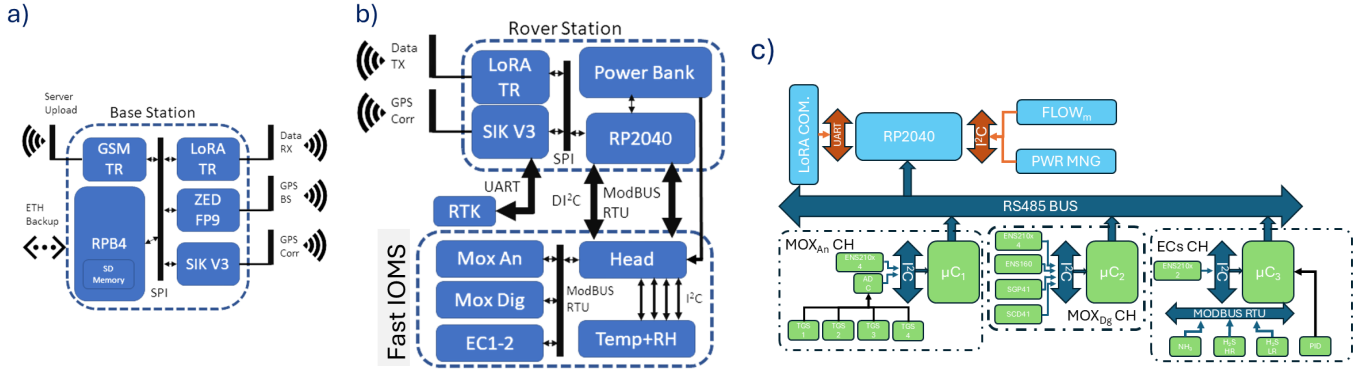


Fig. 1: Graphical description of the Instrumental Odour Monitoring System. a) Block diagram of the Ground Station (GS). It is based on a Raspberry pi 4B+ and communicates with the mobile part of the IOMS via Peer two Peer LoRA connection. It also provide GPS data to the RTK GPS module for corrections and communicates with an external server via GSM router. b) Block diagram of the mobile part of the IOMS. The Rover Station (RS) is placed on the drone and it communicates with the RTK GPS system, controls the power consumption and gets data from the FastIOMS system. This system provides data from three chambers, each with different sensors inside, air flow coming inside the the chambers and temperature and relative humidity of the air in contact with each sensor.

II. IOMS DESCRIPTION

Figures 1 (a), (b) and (c) show the architecture of the novel IOMS. The system is divided in two parts. The mobile part contains the Rover Station (RS) and the Fast IOMS, both mounted on the drone (see figure 2).

III. IOMS PERFORMANCE CHARACTERIZATION

<http://www.latex-community.org/>
<https://tex.stackexchange.com/>

IV. DRONE-MOUNTED IOMS AND FLIGHT PERFORMANCE

See [?], [?], [?], [?], [?] for resources on formatting math into text and additional help in working with \LaTeX .

V. CONCLUSIONS

For some of the remainder of this sample we will use dummy text to fill out paragraphs rather than use live text that may violate a copyright.

Itam, que ipiti sum dem velit la sum et dionet quatibus apitet voloritet audam, qui aliciant voloreicid quaspe volorem ut maximusandit faccum conemporerum aut ellatur, nobis arcimus. Fugit odi ut pliquia incitium latum que cusapere perit molupta eaquearia quod ut optatem poreiur? Quiaerr ovitior suntiant litio bearciur?

Onseque sequaes rector autate minullore nusae nestiberum, sum voluptatio. Et ratem sequiam quaspername nos rem repu-dandae volum consequis nos eium aut as molupta tectum ul-parumquam ut maximillesti consequas quas inctia cum volect-inusa porrum unt eius cusaest exeritatur? Nias es enist fugit pa vollum reium essusam nist et pa aceaqui quo elibusdandis deligendus que nullaci lloreri bla que sa coreriam explacc atiumquos simolorpore, nonprehendunt lam que occum [?] si aut aut maximus eliaeruntia dia sequiamenime natem sendae ipidemp orehend uciisi omnienetus most verum, ommolendi omnimus, est, veni aut ipsa volendelist mo conserum volores estisciis recessi nveles ut poressitatur sitiis ex endi diti volum dolupta aut aut odi as eatquo cullabo remquis toreptum et des accus dolende pores sequas dolores tinust quas expel moditae ne sum quiatiss nis endipie nihilis etum fugiae audi dia quiasit quibus. Ibus el et quatemoluptatque doluptaest et pe volent rem ipidusa eribus utem venimolorae dera qui acea quam etur acruptat. Gias anis doluptaspic tem et aliquis alique inctiuntur?

Sedigent, si aligend elibuscid ut et ium volo tem eictore pellore ritatus ut ut ullatus in con con pere nos ab ium di tem aliqui od magnit repta volectur suntio. Nam isquiante doluptis essit, ut eos suntionsecto debitiur sum ea ipitiis adipit, oditiore, a dolorerempos aut harum ius, atquat.

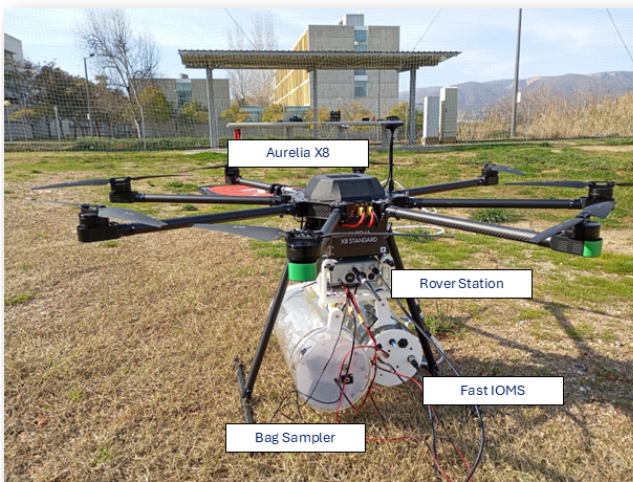


Fig. 2: Novel IOMS mounted on the drone with the Bag Sampler. The Rover Station is placed close to the drone chassis for protection. The Fast IOMS and Bag Sampler air inlets are connected two both 10 meters PTFE tubes.

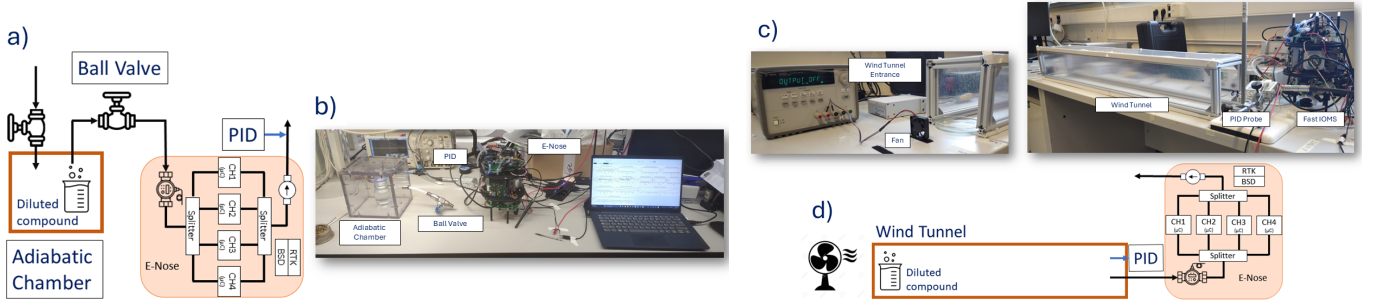


Fig. 3: Experimental setups used for characterizing the Fast IOMS system at the laboratory. a) First setup: the fast IOMS is connected to ball valve acting as a exhaust valve of an adiabatic chamber. The diluted compound is placed inside the chamber and leaved there for 5 minutes with the inlet valve and the exhaust valve closed. After 5 minutes both valves are open and the Fast IOMS inlet is connected to the exhaust valve for data logging. b) Practical realization of the first experimental setup. c) Second setup: The Fast IOMS inlet is placed alongside the probe tip of a 201B miniPID from AURORA Inc. at the end of a wind tunnel. At the entrance of the wind tunnel, a small petri dish with 25mL of the diluted compound with a small fan is placed. The fan is turned on and off in 20 seconds intervals. d) Practical realization of the second setup.

Rum rem ditinti sciendunt voluptuendi sequiae nonsect
orenatur, volores sition ressimil inus solut ea volum harumqui
to see(1) mint aut quat eos explis ad quodi debis deliqui aspel
earcius.

$$x = \sum_{i=0}^n 2iQ. \quad (1)$$

Alis nime volorempera perferi sitio denim repudae pre
ducilit atatet volecte ssimillorae dolore, ut pel ipsa nonse-
quiam in re nus maiost et que dolor sunt eturita tibusanis
eatent a aut et dio blaudit reptibu scipitem liquia consequodi
od unto ipsae. Et enitia vel et experferum quiat harum sa
net faccae dolut voloria nem. Bus ut labo. Ita eum repraer
rovitia samendit aut et volupta tecupti busant omni quiae
porro que nossimodic temquis anto blacita conse nis am, que
ereperum eumquam quaescil imenisci quae magnimos recus
ilibeaque cum etum iliate prae parumquatemo blaceaquiam
quundia dit apienditem rerit re eici quaes eos sinvers pelecabo.
Namendignis as exerupit aut magnim ium illabor roratecte plic
tem res apiscipsam et vernat untur a deliquaest que non cus
eat ea dolupiducim fugiam volum hil ius dolo eaquis sitis
aut landesto quo corerest et auditaquas ditae valoribus, qui
optaspis exero cusa am, ut plibus.

VI. SOME COMMON ELEMENTS

A. Sections and Subsections

Enumeration of section headings is desirable, but not required. When numbered, please be consistent throughout the article, that is, all headings and all levels of section headings in the article should be enumerated. Primary headings are designated with Roman numerals, secondary with capital letters, tertiary with Arabic numbers; and quaternary with lowercase letters. Reference and Acknowledgment headings are unlike all other section headings in text. They are never enumerated. They are simply primary headings without labels, regardless of whether the other headings in the article are enumerated.

B. Citations to the Bibliography

The coding for the citations is made with the \LaTeX `\cite` command. This will display as: see [?].

For multiple citations code as follows:
`\cite{ref1,ref2,ref3}` which will produce [?], [?], [?]. For reference ranges that are not consecutive code as `\cite{ref1,ref2,ref3,ref9}` which will produce [?], [?], [?], [?]

C. Lists

In this section, we will consider three types of lists: simple unnumbered, numbered, and bulleted. There have been many options added to IEEEtran to enhance the creation of lists. If your lists are more complex than those shown below, please refer to the original “IEEEtran_HOWTO.pdf” for additional options.

A plain unnumbered list:

bare_jrnl.tex
bare_conf.tex
bare_jrnl_compsoc.tex
bare_conf_compsoc.tex
bare_jrnl_comsoc.tex

A simple numbered list:

- 1) bare_jrnl.tex
- 2) bare_conf.tex
- 3) bare_jrnl_compsoc.tex
- 4) bare_conf_compsoc.tex
- 5) bare_jrnl_comsoc.tex

A simple bulleted list:

- bare_jrnl.tex
- bare_conf.tex
- bare_jrnl_compsoc.tex
- bare_conf_compsoc.tex
- bare_jrnl_comsoc.tex



Fig. 4: Simulation results for the network.

TABLE I: An Example of a Table

One	Two
Three	Four

D. Figures

Fig. 1 is an example of a floating figure using the `graphicx` package. Note that `\label` must occur AFTER (or within) `\caption`. For figures, `\caption` should occur after the `\includegraphics`.

Fig. 2(a) and 2(b) is an example of a double column floating figure using two subfigures. (The `subfig.sty` package must be loaded for this to work.) The subfigure `\label` commands are set within each `subfloat` command, and the `\label` for the overall figure must come after `\caption`. `\hfil` is used as a separator to get equal spacing. The combined width of all the parts of the figure should do not exceed the text width or a line break will occur.

Note that often IEEE papers with multi-part figures do not place the labels within the image itself (using the optional argument to `\subfloat[]`), but instead will reference/describe all of them (a), (b), etc., within the main caption. Be aware that for `subfig.sty` to generate the (a), (b), etc., subfigure labels, the optional argument to `\subfloat` must be present. If a subcaption is not desired, leave its contents blank, e.g., `\subfloat[]`.

VII. TABLES

Note that, for IEEE-style tables, the `\caption` command should come BEFORE the table. Table captions use title case. Articles (a, an, the), coordinating conjunctions (and, but, for, or, nor), and most short prepositions are lowercase unless they are the first or last word. Table text will default to `\footnotesize` as the IEEE normally uses this smaller font for tables. The `\label` must come after `\caption` as always.

VIII. ALGORITHMS

Algorithms should be numbered and include a short title. They are set off from the text with rules above and below the title and after the last line.

Algorithm 1 Weighted Tanimoto ELM.

TRAIN($\mathbf{X}\mathbf{T}$)

```

select randomly  $W \subset \mathbf{X}$ 
 $N_t \leftarrow |\{i : t_i = t\}|$  for  $t = -1, +1$ 
 $B_i \leftarrow \sqrt{\text{MAX}(N_{-1}, N_{+1})/N_{t_i}}$  for  $i = 1, \dots, N$ 
 $\hat{\mathbf{H}} \leftarrow B \cdot (\mathbf{X}^T \mathbf{W}) / (\|\mathbf{X}\| + \|\mathbf{W}\| - \mathbf{X}^T \mathbf{W})$ 
 $\beta \leftarrow (I/C + \hat{\mathbf{H}}^T \hat{\mathbf{H}})^{-1} (\hat{\mathbf{H}}^T B \cdot \mathbf{T})$ 
return  $\mathbf{W}, \beta$ 

```

PREDICT(\mathbf{X})

```

 $\mathbf{H} \leftarrow (\mathbf{X}^T \mathbf{W}) / (\|\mathbf{X}\| + \|\mathbf{W}\| - \mathbf{X}^T \mathbf{W})$ 
return  $\text{SIGN}(\mathbf{H}\beta)$ 

```

Que sunt eum lam eos si dic to estist, culluptium quid qui nestrum nobis reiumquiatur minimus minctem. Ro moluptat fuga. Itatquiam ut laborpo rersped exceres vollandi repudaerem. Ulparci sunt, qui doluptaquis sumquia ndestiu sapient iorepella sunti veribus. Ro moluptat fuga. Itatquiam ut laborpo rersped exceres vollandi repudaerem.

IX. MATHEMATICAL TYPOGRAPHY AND WHY IT MATTERS

Typographical conventions for mathematical formulas have been developed to **provide uniformity and clarity of presentation across mathematical texts**. This enables the readers of those texts to both understand the author's ideas and to grasp new concepts quickly. While software such as \LaTeX and MathType[®] can produce aesthetically pleasing math when used properly, it is also very easy to misuse the software, potentially resulting in incorrect math display.

IEEE aims to provide authors with the proper guidance on mathematical typesetting style and assist them in writing the best possible article. As such, IEEE has assembled a set of examples of good and bad mathematical typesetting [?], [?], [?], [?], [?].

Further examples can be found at <http://journals.ieeeauthorcenter.ieee.org/wp-content/uploads/sites/7/IEEE-Math-Typesetting-Guide-for-LaTeX-Users.pdf>

A. Display Equations

The simple display equation example shown below uses the “equation” environment. To number the equations, use the `\label` macro to create an identifier for the equation. LaTeX will automatically number the equation for you.

$$x = \sum_{i=0}^n 2iQ. \quad (2)$$

is coded as follows:

```

\begin{equation}
\label{deqn_ex1}
x = \sum_{i=0}^n 2\{i\} Q.
\end{equation}

```

To reference this equation in the text use the `\ref` macro. Please see (2) is coded as follows:



Fig. 5: Dae. Ad quatur autat ut porepel itemoles dolor autem fuga. Bus quia con nessunti as remo di quatus non perum que nimus. (a) Case I. (b) Case II.

Please see (\ref{deqn_ex1})

B. Equation Numbering

Consecutive Numbering: Equations within an article are numbered consecutively from the beginning of the article to the end, i.e., (1), (2), (3), (4), (5), etc. Do not use roman numerals or section numbers for equation numbering.

Appendix Equations: The continuation of consecutively numbered equations is best in the Appendix, but numbering as (A1), (A2), etc., is permissible.

Hyphens and Periods: Hyphens and periods should not be used in equation numbers, i.e., use (1a) rather than (1-a) and (2a) rather than (2.a) for subequations. This should be consistent throughout the article.

C. Multi-Line Equations and Alignment

Here we show several examples of multi-line equations and proper alignments.

A single equation that must break over multiple lines due to length with no specific alignment.

The first line of this example

The second line of this example

The third line of this example (3)

is coded as:

```
\begin{multline}
\text{The first line of this example}\\
\text{The second line of this example}\\
\text{The third line of this example}
\end{multline}
```

A single equation with multiple lines aligned at the = signs

$$a = c + d \quad (4)$$

$$b = e + f \quad (5)$$

is coded as:

```
\begin{align}
a &= c+d \\
b &= e+f
\end{align}
```

The align environment can align on multiple points as shown in the following example:

$$x = y \quad X = Y \quad a = bc \quad (6)$$

$$x' = y' \quad X' = Y' \quad a' = bz \quad (7)$$

is coded as:

```
\begin{align}
x &= y & X &= Y & a &= bc \\
x' &= y' & X' &= Y' & a' &= bz
\end{align}
```

D. Subnumbering

The amsmath package provides a subequations environment to facilitate subnumbering. An example:

$$f = g \quad (8a)$$

$$f' = g' \quad (8b)$$

$$\mathcal{L}f = \mathcal{L}g \quad (8c)$$

is coded as:

```
\begin{subequations}\label{eq:2}
\begin{align}
f&=g \label{eq:2A}\\
f'&=g' \label{eq:2B}\\
\mathcal{L}f &= \mathcal{L}g \label{eq:2C}
\end{align}
\end{subequations}
```

E. Matrices

There are several useful matrix environments that can save you some keystrokes. See the example coding below and the output.

A simple matrix:

$$\begin{pmatrix} 0 & 1 \\ 1 & 0 \end{pmatrix} \quad (9)$$

is coded as:

```
\begin{equation}
\begin{matrix} 0 & 1 \\ 1 & 0 \end{matrix} \\
\end{equation}
```

A matrix with parenthesis

$$\begin{pmatrix} 0 & -i \\ i & 0 \end{pmatrix} \quad (10)$$

is coded as:

```
\begin{equation}
\begin{pmatrix} 0 & -i \\ i & 0 \end{pmatrix} \\
\end{equation}
```

A matrix with square brackets

$$\begin{bmatrix} 0 & -1 \\ 1 & 0 \end{bmatrix} \quad (11)$$

is coded as:

```
\begin{equation}
\begin{bmatrix} 0 & -1 \\ 1 & 0 \end{bmatrix} \\
\end{equation}
```

A matrix with curly braces

$$\begin{Bmatrix} 1 & 0 \\ 0 & -1 \end{Bmatrix} \quad (12)$$

is coded as:

```
\begin{equation}
\begin{Bmatrix} 1 & 0 \\ 0 & -1 \end{Bmatrix} \\
\end{equation}
```

A matrix with single verticals

$$\begin{vmatrix} a & b \\ c & d \end{vmatrix} \quad (13)$$

is coded as:

```
\begin{equation}
\begin{vmatrix} a & b \\ c & d \end{vmatrix} \\
\end{equation}
```

A matrix with double verticals

$$\left\| \begin{matrix} i & 0 \\ 0 & -i \end{matrix} \right\| \quad (14)$$

is coded as:

```
\begin{equation}
\begin{vmatrix} i & 0 \\ 0 & -i \end{vmatrix} \\
\end{equation}
```

F. Arrays

The array environment allows you some options for matrix-like equations. You will have to manually key the fences, but there are other options for alignment of the columns and for setting horizontal and vertical rules. The argument to array controls alignment and placement of vertical rules.

A simple array

$$\left(\begin{array}{cccc} a+b+c & uv & x-y & 27 \\ a+b & u+v & z & 134 \end{array} \right) \quad (15)$$

is coded as:

```
\begin{equation}
\left(
\begin{array}{cccc}
a+b+c & uv & x-y & 27 \\
a+b & u+v & z & 134
\end{array}
\right) \\
\end{equation}
```

A slight variation on this to better align the numbers in the last column

$$\left(\begin{array}{cccc} a+b+c & uv & x-y & 27 \\ a+b & u+v & z & 134 \end{array} \right) \quad (16)$$

is coded as:

```
\begin{equation}
\left(
\begin{array}{cccc}
a+b+c & uv & x-y & 27 \\
a+b & u+v & z & 134
\end{array}
\right) \\
\end{equation}
```

An array with vertical and horizontal rules

$$\left(\begin{array}{c|c|c|c} a+b+c & uv & x-y & 27 \\ a+b & u+v & z & 134 \end{array} \right) \quad (17)$$

is coded as:

```
\begin{equation}
\left(
\begin{array}{c|c|c|c}
a+b+c & uv & x-y & 27 \\
a+b & u+v & z & 134
\end{array}
\right) \\
\end{equation}
```

Note the argument now has the pipe ”|” included to indicate the placement of the vertical rules.

G. Cases Structures

Many times cases can be miscoded using the wrong environment, i.e., `array`. Using the `cases` environment will save keystrokes (from not having to type the `\left\lbracket`) and automatically provide the correct column alignment.

$$z_m(t) = \begin{cases} 1, & \text{if } \beta_m(t) \\ 0, & \text{otherwise.} \end{cases}$$

is coded as follows:

```
\begin{equation*}
\{z_m(t)\} =
\begin{cases}
1, & \text{\text{if}} \ \{\beta_m(t)\}, \\
0, & \text{\text{otherwise.}}
\end{cases}
\end{equation*}
```

Note that the “&” is used to mark the tabular alignment. This is important to get proper column alignment. Do not use `\quad` or other fixed spaces to try and align the columns. Also, note the use of the `\text` macro for text elements such as “if” and “otherwise.”

H. Function Formatting in Equations

Often, there is an easy way to properly format most common functions. Use of the `\` in front of the function name will in most cases, provide the correct formatting. When this does not work, the following example provides a solution using the `\text` macro:

$$d_R^{KM} = \arg \min_{d_i^{KM}} \{d_1^{KM}, \dots, d_6^{KM}\}.$$

is coded as follows:

```
\begin{equation*}
d_{\text{R}}^{\text{KM}} = \underset{\{\text{d}_{\text{1}}^{\text{KM}}\}}{\text{\text{arg min}}} \ \{\text{d}_{\text{1}}^{\text{KM}}, \\
\text{\ldots}, \text{d}_{\text{6}}^{\text{KM}}\}.
\end{equation*}
```

I. Text Acronyms Inside Equations

This example shows where the acronym “MSE” is coded using `\text{\{}` to match how it appears in the text.

$$\text{MSE} = \frac{1}{n} \sum_{i=1}^n (Y_i - \hat{Y}_i)^2$$

```
\begin{equation*}
\text{\text{MSE}} = \frac{1}{n} \sum_{i=1}^n (Y_{\text{i}} - \hat{Y}_{\text{i}})^2
\end{equation*}
```

X. CONCLUSION

The conclusion goes here.

ACKNOWLEDGMENTS

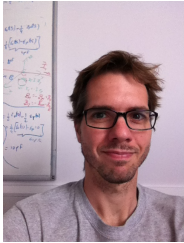
The authors would also thank people helping during the measurement campaigns. M.Sc. Alessandro Benegiamo, M.Sc. Veronica Vila, Eva Martín and M.Sc. Eduardo “Lalo” Caballero were part of the team that allow this work to achieve excellence.

REFERENCES

- [1] K. Persaud, “Medical applications of odor-sensing devices,” *International Journal of Lower Extremity Wounds*, vol. 4, no. 1, pp. 50–56, 2005.
- [2] L. Capelli, S. Sironi, and R. Del Rosso, “Electronic noses for environmental monitoring applications,” *Sensors (Basel)*, vol. 14, no. 11, pp. 19 979–2007, 2014.
- [3] V. Di Lecce, D. Petruzzelli, C. Guaragnella, A. Cardellicchio, G. Dentamaro, A. Quarto, D. Soldo, and R. Dario, “Real-time monitoring system for urban wastewater,” in *2017 IEEE Workshop on Environmental, Energy, and Structural Monitoring Systems (EESMS)*. IEEE, 2017, pp. 1–5.
- [4] A. Blanco-Rodriguez, V. Camara, F. Campo, L. Becheran, A. Duran, V. Vieira, H. de Melo, and A. Garcia-Ramirez, “Development of an electronic nose to characterize odours emitted from different stages in a wastewater treatment plant,” *Water Research*, vol. 134, pp. 92–100, 2018.
- [5] F. Cangialosi, G. Intini, and D. Colucci, “On line monitoring of odour nuisance at a sanitary landfill for non-hazardous waste,” *Chem. Eng. Trans*, vol. 68, pp. 127–132, 2018.
- [6] M. Daelman, E. van Voorthuizen, U. van Dongen, E. Volcke, and M. van Loosdrecht, “Methane emission during municipal wastewater treatment,” *Water Research*, vol. 46, no. 11, pp. 3657–3670, 2012.
- [7] S. Prudenza, C. Bax, and L. Capelli, “Implementation of an electronic nose for real-time identification of odour emission peaks at a wastewater treatment plant,” *Heliyon*, vol. 9, no. 10, 2023.
- [8] D. Cipriano and L. Capelli, “Evolution of electronic noses from research objects to engineered environmental odour monitoring systems: A review of standardization approaches,” *Biosensors*, vol. 9, no. 2, p. 75, 2019.
- [9] S. Deshmukh, R. Bandyopadhyay, N. Bhattacharyya, R. Pandey, and A. Jana, “Application of electronic nose for industrial odors and gaseous emissions measurement and monitoring—an overview,” *Talanta*, vol. 144, pp. 329–340, 2015.
- [10] C. Ratti, C. Bax, B. Lotesoriere, and L. Capelli, “Real-time monitoring of odour emissions at the fence-line of a waste treatment plant by instrumental odour monitoring systems: Focus on training methods,” *Sensors*, vol. 24, no. 11, p. 3506, 2024.
- [11] T. Pobkrut, T. Eamsa-Ard, and T. Kerdcharoen, “Sensor drone for aerial odor mapping for agriculture and security services,” in *2016 13th International Conference on Electrical Engineering/Electronics, Computer, Telecommunications and Information Technology (ECTI-CON)*. IEEE, 2016, pp. 1–5.
- [12] J. Burgués, M. Deseada Esclapez, S. Donate, and S. Marco, “Rhinos: a lightweight portable electronic nose for real-time odor quantification in wastewater treatment plants,” *iScience*, vol. 24, no. 12, 2021.
- [13] J. Burgués, S. Donate, M. Esclapez, L. Sauco, and S. Marco, “Characterization of odour emissions in a wastewater treatment plant using a drone-based chemical sensor system,” *Science of the Total Environment*, vol. 846, p. 15729, 2022.
- [14] G. Tassielli, L. Cananà, and M. Spalatro, “Detection of methane leaks via a drone-based system for sustainable landfills and oil and gas facilities: Effect of different variables on the background-noise measurement,” *Sustainability*, vol. 16, no. 17, p. 7748, 2024.
- [15] M. Yandouzi, M. Grari, M. Berrahal, I. Idrissi, O. Moussaoui, M. Azizi, K. Ghoumid, and A. Elmiad, “Investigation of combining deep learning object recognition with drones for forest fire detection and monitoring,” *International Journal of Advanced Computer Science and Applications*, vol. 14, no. 3, 2023.
- [16] J. Burgués and S. Marco, “Drone-based monitoring of environmental gases,” in *Air Quality Networks, Environmental Informatics and Modeling*, S. De Vito *et al.*, Eds. Springer Nature Switzerland AG, 2023, pp. 115–136.
- [17] J. Higués, L. Valdez, and S. Marco, “High-bandwidth e-nose for rapid tracking of turbulent plumes,” in *2019 IEEE International Symposium on Olfaction and Electronic Nose (ISOEN)*. Fukuoka, Japan: IEEE, 2019, pp. 1–3.

- [18] F. Cangialosi, E. Bruno, and A. Fornaro, "Integrating citizen science and machine learning algorithms for the recognition of odour classes nearby a wastewater treatment plant," *Chemical Engineering Transactions*, vol. 95, pp. 25–30, Oct 2022.
- [19] A. Benegiamo, J. Burgués, J. Alonso-Valdesueiro, B. Lotesoriere, L. Terrén, L. Saucó, M. Esclapez, S. Doñate, A. Gutiérrez-Gálvez, and S. Marco, "Optimization of a drone-based system for instrumental odor monitoring using feature selection," *Proceedings*, vol. 97, p. 109, 2024.
- [20] J. Alonso-Valdesueiro, S. Marco, and A. Gutierrez-Galvez, "Drone-nose: drone-embedded measurement platform for odour monitoring," in *IEEE International Symposium on Olfaction and Electronic Nose, ISOEN 2024, Grapevine, TX, USA, May 12-15, 2024*. IEEE, 2024, pp. 1–3. [Online]. Available: <https://doi.org/10.1109/ISOEN61239.2024.10556083>

XI. BIOGRAPHIES



Javier Alonso-Valdesueiro was born in Madrid, Spain, in 1980. He received his Telecommunications Engineering degree from the University of Alcalá, Madrid, in 2006, and his Ph.D. degree from the Polytechnic University of Catalonia, Barcelona, in 2011. From 2012 to 2020, he worked on developing electronic instrumentation for NMR experiments, initially at the C.E.A Center in France, followed by the University of Southampton in the UK, and later as a Marie Skłodowska-Curie Fellow at the University of the Basque Country (UPV/EHU). Over

the past four years, he has advanced his career as an RF and instrumentation engineer in both private companies and public research centers, including TECNALIA Innovation Foundation and the Institute of Biomedical Engineering of Catalonia. Recently, he has been appointed as Assistant Professor in the Department of Electronic and Biomedical Engineering at the University of Barcelona.