Drone Based Intelligent Magnetic Sensing System and Metallic Anomaly Detection System

A Project Report Submitted to

Smart India Hackathon

Bachelor of Engineering

In

Electronics & Communication

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September 2023

ACKNOWLEDGEMENT

We would like to express our sincere gratitude and appreciation to our guide, **Mr. Abhay Upadhyay** and **Mr.Dhaval Patel** for giving us a chance to work with them despite his many other academic and professional commitments and also for their supervision, advice, guidance, encouragement, dedicated effort, criticism and patience.

It's a pleasure for us to be part of **Smart India Hackathon** and therefore we would like to thank all the teaching and non-teaching staff members of **L.D. College of Engineering** for their support. Their inspiration and encouragement have led us to come with a successful task.

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ABSTRACT

In the era of advanced technology, our project introduces a Drone-Based Magnetic Sensing System. This system utilizes drones to detect magnetic anomalies over land and sea, offering enhanced defense and security capabilities.

Our goal is to create a smart, independent drone system that can find and categorize magnetic anomalies while compensating for its own magnetic interference. We've designed a Portable Drone Control Module with cutting-edge algorithms to achieve this.

Our project explores ways to identify metallic objects with magnetic anomalies, improving the system's accuracy. We've developed a customized drone with a magnetic sensor and compensation techniques. We use open-source geomagnetic data for accurate anomaly classification.

Real-world data demonstrates the system's effectiveness. Our project has broad applications and represents an important step in defense and security technology.

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CHAPTER 1: INTRODUCTION

1.1 Background and Problem Statement

In the realm of modern warfare and security operations, the detection, identification, and classification of metallic objects are of paramount importance. Many military threats are concealed beneath the earth's surface or within complex terrains, making their identification challenging. To address this crucial need, we present a groundbreaking project that leverages magnetic signatures for military applications.

The project centers on the concept of magnetic signatures, which arise due to the presence of ferromagnetic materials in metallic objects. These materials induce localized magnetic disturbances in the Earth's magnetic field, creating distinctive patterns known as magnetic signatures.

The primary challenge we address is two-fold: firstly, the need for accurate magnetic field measurement, and secondly, the identification and classification of metallic magnetic anomalies from open-source geomagnetic data. This project has profound implications for enhancing military operations by providing a state-of-the-art solution for detecting concealed metallic threats.

1.2 Objectives of the Project

The overarching objectives of this project are as follows:

1. **Develop a Military-Grade Drone-Based Magnetic Sensing System**: Design and build a robust medium-sized quad-copter drone, specifically tailored for military applications. The drone will be equipped with telemetry, GPS, a camera, and a high-precision flux-gate-like magnetometer.

2. **Magnetic Field Assessment for Military Precision**: Create advanced algorithms for precise magnetic field assessment in specific operational areas, compensating for the drone's self-magnetic field.

3. **Concealed Threat Detection:** Implement cutting-edge methodologies for the swift identification of concealed metallic threats within designated military zones.

4. **Integration with Military Geomagnetic Data:** Seamlessly integrate military geomagnetic data to enhance threat identification and classification accuracy.

1.3 Significance and Scope

The significance of this project lies in its potential to revolutionize military operations:
Improving Security: The project offers a critical tool for identifying and neutralizing concealed metallic threats, enhancing military security.

Enhancing Efficiency:It aids in the rapid identification of landmines, improvised explosive devices (IEDs), and other hidden threats, reducing response times and risks to personnel.

The scope of this project encompasses the development and implementation of a comprehensive military-grade Drone-Based Magnetic Sensing System. This includes the entire lifecycle, from hardware configuration to data acquisition, processing, and specialized threat detection algorithms.

1.4 Project Overview

This report provides a comprehensive account of the development and deployment of the Military-Grade Drone-Based Magnetic Sensing System for the specific purpose of enhancing military security. The report is structured as follows:

This project report aims to provide a detailed insight into the capabilities and potential military applications of the Drone-Based Magnetic Sensing System, equipping military personnel with advanced tools for enhanced security and threat detection.

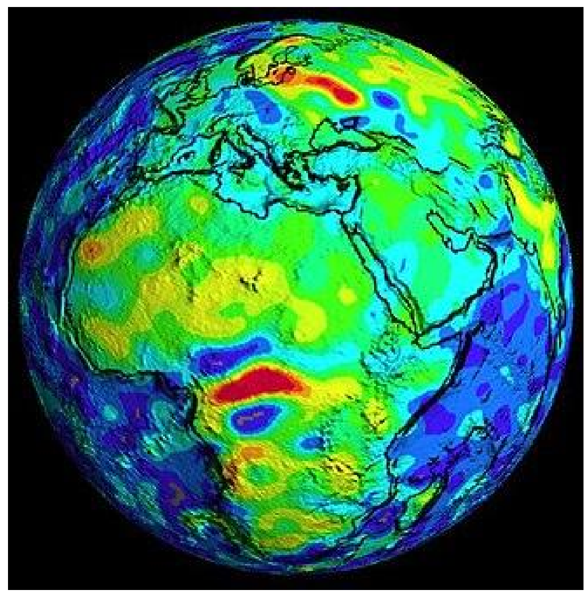
CHAPTER 2: TECHNOLOGY BACKGROUND

2.1 Magnetic Signature and Geomagnetic Anomalies

2.1.1 Ferromagnetic Materials

Ferromagnetic materials are a class of substances with unique magnetic properties. At the atomic level, they possess magnetic moments that align spontaneously when exposed to an external magnetic field. This alignment results in the creation of a magnetic field within the material. In the context of metallic objects, which are often constructed using ferromagnetic materials, these materials induce magnetic disturbances in the surrounding environment. These disturbances, commonly referred to as magnetic signatures, can vary in intensity and spatial distribution, making them valuable for detecting and identifying metallic objects.

2.1.2 Geomagnetic Anomalies



Geomagnetic anomalies represent variations in the Earth's magnetic field strength and direction. These anomalies can occur due to a variety of factors, both natural and anthropogenic. Natural sources of geomagnetic anomalies include geological features such as ore bodies, fault lines, and volcanic activity. Additionally, meteorological conditions, such as solar storms, can influence geomagnetic readings. Anthropogenic sources, on the other hand, encompass human-made metallic objects like buried infrastructure or military equipment. Understanding geomagnetic anomalies is pivotal in the context of magnetic signature analysis. These anomalies serve as the basis for detecting metallic objects, as deviations from the expected geomagnetic field provide valuable clues about the presence and nature of concealed objects.

2.2 Existing Drone Technology and Applications

2.2.1 Drone Technology Evolution

The evolution of drone technology has been marked by significant advancements in both hardware and software components. Early drones were primarily used for surveillance and reconnaissance, equipped with basic cameras and telemetry systems. However, modern drones have undergone remarkable transformations.

1. **Sensor Integration:** One of the key developments in drone technology is the integration of advanced sensors. These sensors include high-resolution cameras, LiDAR (Light Detection and Ranging) systems for 3D mapping, multispectral cameras for environmental monitoring, and, most relevant to our project, magnetometers for magnetic field measurement. These sensors have expanded the capabilities of drones, enabling them to collect diverse data types simultaneously.

2. **Autonomous Flight:** Drones have evolved to perform increasingly autonomous tasks. Advanced flight control algorithms, GPS navigation, and obstacle avoidance systems allow drones to execute complex missions with minimal human intervention. This autonomy enhances their usability in various applications, including military operations.

2.2.2 Military Drone Applications

The military sector has embraced drone technology for a wide range of applications. Drones, often referred to as Unmanned Aerial Vehicles (UAVs) or Unmanned Aircraft Systems (UAS), have proven invaluable in enhancing military capabilities.

1. **Surveillance and Reconnaissance:** Military drones are extensively used for surveillance and reconnaissance missions. Equipped with high-resolution cameras and advanced imaging systems, they provide real-time aerial views of operational areas, aiding in intelligence gathering.

2. **Threat Detection:** Drones play a crucial role in threat detection, particularly in identifying concealed threats such as improvised explosive devices (IEDs) and landmines. The ability to access remote or hazardous areas makes drones ideal for this task.

3. **Enhanced Situational Awareness:** By providing aerial perspectives, drones enhance situational awareness for military personnel. This improved awareness contributes to better decision-making and reduced risks.

These applications underscore the relevance of drone technology in the military context and its potential to enhance security and threat detection.

2.3 Self-Magnetic Field Compensation Techniques

2.3.1 Self-Magnetic Field Challenges

The operation of drones equipped with magnetometers introduces a unique challenge—self-magnetic field interference. Drones, like all metallic objects, possess their own magnetic properties. These properties can distort magnetic field measurements, leading to inaccuracies in detecting external magnetic anomalies.

Compensation for the self-magnetic field is crucial to obtain precise magnetic anomaly data. Failure to address this challenge can result in false positives or negatives during threat detection missions. Several factors contribute to the complexity of self-magnetic field interference, including the drone's size, shape, and the magnetic properties of its components.

2.3.2 Compensation Algorithms

A range of compensation algorithms has been developed to address self-magnetic field interference. These algorithms aim to estimate the drone's self-magnetic field and subtract it from the overall magnetic field measurements. Common compensation techniques include:

1. **Hard Iron Calibration:** This method corrects for the drone's hard iron effects, which result from permanent magnetic sources onboard. By measuring these effects and subtracting them from the data, hard iron calibration compensates for fixed magnetic interference.

2. **Soft Iron Calibration:** Soft iron calibration addresses distortions caused by the drone's structure and materials. It involves transforming the data to correct for the varying magnetic susceptibility of different parts of the drone.

3. **Advanced Machine Learning Algorithms:** Some approaches utilize machine learning techniques, such as neural networks, to model and compensate for the self-magnetic field. These algorithms can adapt to changing conditions and improve compensation accuracy.

Understanding the intricacies of self-magnetic field challenges and compensation techniques is fundamental to our project's success. By implementing effective compensation algorithms, we aim to enhance the accuracy of our magnetic anomaly detection system.

2.4 Anomaly Detection Algorithms

2.4.1 Gridded Magnetic Algorithm

Central to our project's success is the Gridded Magnetic Algorithm, which forms the backbone of our magnetic anomaly detection strategy. This algorithm operates by dividing the survey area into a grid, systematically comparing measured magnetic field strength with expected values derived from open-source geomagnetic data. The result is a comprehensive magnetic anomaly map, with areas of significant deviation highlighted for further investigation.

2.4.2 Gradient-Based Anomaly Detection Algorithm

The Gradient-Based Anomaly Detection Algorithm is another vital component of our project. This algorithm relies on calculating gradient magnitudes of the measured magnetic field. Anomalies are detected by identifying significant variations in gradient values.

2.5 Geo-spatial Data Analysis Tools

2.5.1 Open-Source Geomagnetic Data

Open-source geomagnetic data sources provide critical reference information for our project. These datasets encompass magnetic field measurements collected globally and are freely accessible. Key sources include government agencies, research institutions, and international organizations. Access to such data allows us to establish a baseline for expected magnetic field values across different geographical regions. This reference data forms the basis for anomaly detection and classification.

2.5.2 Geo-spatial Analysis Software

Geo-spatial analysis software plays a pivotal role in our project's data processing pipeline. Geographic Information Systems (GIS) software, such as Quantum GIS (QGIS) and Esri ArcGIS, offers powerful tools for manipulating, visualizing, and analyzing magnetic field data. These software packages facilitate the integration of various data sources, including open-source geomagnetic data, drone-collected measurements, and anomaly detection results. They enable us to create detailed maps, perform spatial analysis, and generate actionable insights for military applications.

CHAPTER 3: PROJECT METHODOLOGY

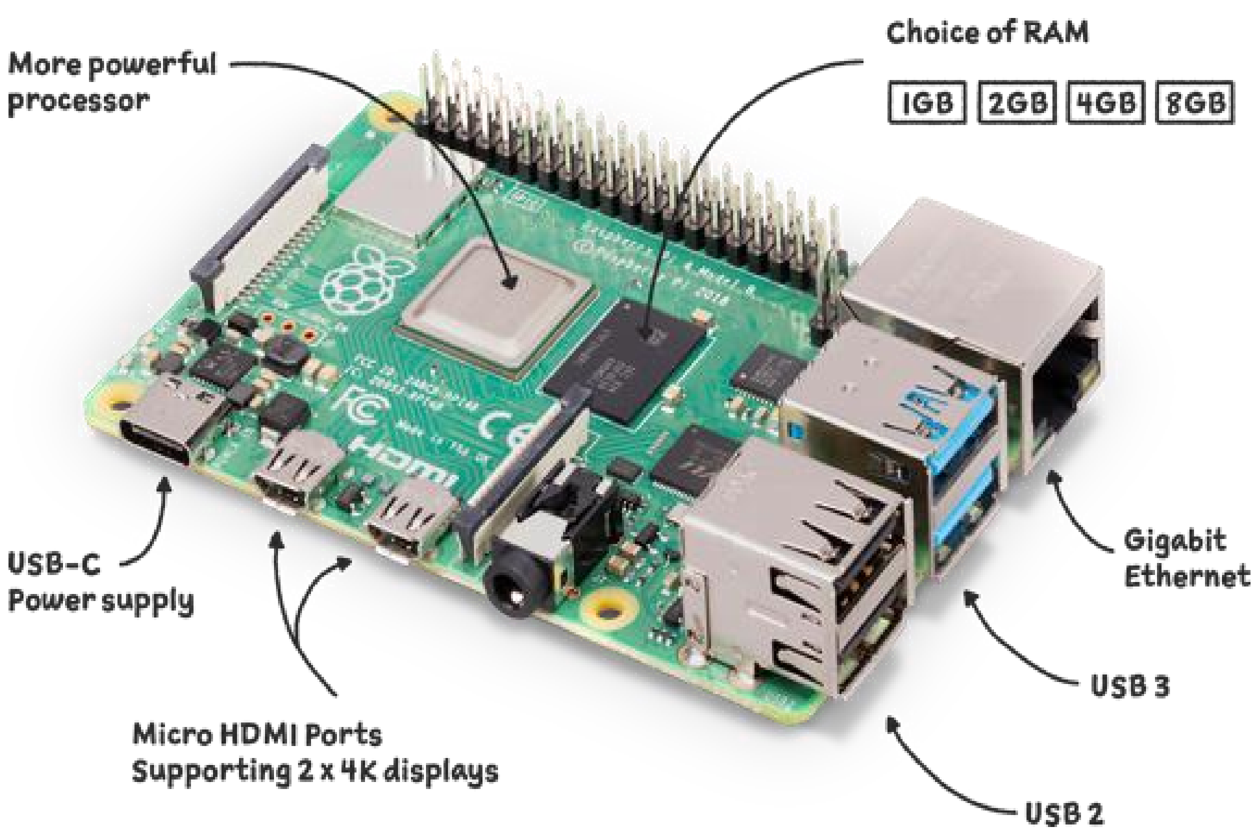
3.1 System Design and Configuration

3.1.1 Drone Hardware Selection

The success of our project hinges on meticulous hardware selection, tailored to meet the demanding requirements of military applications. Factors like payload capacity, endurance, and sensor integration capabilities were scrutinized. Ultimately, we chose a **medium-sized quad-copter drone equipped with telemetry, GPS, a camera, and a high-precision flux-gate-like magnetometer.** This choice aligns perfectly with our project's objectives, offering the versatility and reliability necessary for military missions.

3.1.2 Onboard Control System

The onboard control system, with a Raspberry Pi at its core, plays a pivotal role in orchestrating the project's complex operations. This central hub seamlessly manages telemetry, GPS, camera, and magnetometer functionalities. Leveraging UGCS-like software for flight path planning, we ensure precision in drone control during data acquisition missions. The Raspberry Pi's computational prowess is harnessed for real-time data processing, further enhancing the project's efficiency.



3.2 Data Acquisition and Processing

3.2.1 GPS and Magnetometer Data Collection

Our data acquisition strategy involves the continuous capture of critical information during drone flights. The GPS sensor records precise geographic coordinates, ensuring that every data point is associated with its specific location. Simultaneously, the magnetometer diligently captures magnetic field data at predetermined coordinates, allowing us to build a comprehensive data-set. Careful consideration is given to data logging frequency and duration, ensuring that no pertinent information is missed.

3.2.2 Error Handling Mechanisms

Maintaining the integrity of acquired data is non-negotiable. Robust error handling mechanisms are deeply embedded within the data collection process. These mechanisms enable real-time anomaly detection and correction, swiftly addressing any data anomalies or sensor malfunctions that may arise. Through meticulous error handling, we guarantee the reliability and accuracy of our datasets, forming the foundation for precise magnetic anomaly analysis.

3.3 Self-Magnetic Field Compensation

3.3.1 Self-Magnetic Field Estimation Algorithms

The interference caused by a drone's self-magnetic field is a critical challenge. To overcome this, we employ advanced self-magnetic field estimation algorithms. These algorithms leverage the drone's physical characteristics, including size, shape, and magnetic properties, to calculate and subsequently subtract the self-magnetic field from the overall magnetic measurements. This critical step significantly enhances measurement accuracy, ensuring that detected anomalies are genuine and not influenced by the drone's presence.

3.3.2 Implementation and Testing

Practical implementation of self-magnetic field compensation occurs during data processing at the ground station. It's here that the algorithms come to life, enabling the precise correction of magnetic field measurements. Rigorous testing and validation procedures are conducted to ensure the effectiveness of these compensation techniques. Through extensive testing, we guarantee the accuracy of our measurements, a cornerstone of magnetic anomaly detection.

3.4 Magnetic Anomaly Detection

3.4.1 Gridded Magnetic Algorithm Implementation

The Gridded Magnetic Algorithm is a fundamental component of our project's anomaly detection system. This algorithm divides the study area into a grid of smaller cells and compares measured magnetic field values within each cell to expected values derived from open-source geomagnetic data.

Key Steps:

1. Grid Creation: The study area is divided into a grid, with each cell representing a specific geographic region.
2. Expected Field Values: For each cell, the algorithm calculates the expected magnetic field values based on open-source geomagnetic data corresponding to that location.
3. Measured Field Values: The drone measures the magnetic field within each cell during its flight.
4. Comparison: Measured magnetic field values are compared to the expected values. Deviations beyond a predefined threshold indicate potential anomalies.
5. Anomaly Mapping: Detected anomalies are mapped, enabling visual identification of regions with magnetic disturbances.

3.4.2 Gradient-Based Anomaly Detection Algorithm

The Gradient-Based Anomaly Detection Algorithm is another vital component of our project. This algorithm relies on calculating gradient magnitudes of the measured magnetic field. Anomalies are detected by identifying significant variations in gradient values.

Key Steps:

1. Gradient Calculation: The algorithm computes the gradient magnitude at each measurement point within the study area.
2. Expected Gradient Values: Expected gradient values are determined based on open-source geomagnetic data for the corresponding locations.
3. Gradient Comparison: Measured gradient values are compared to expected values. Significant deviations indicate potential anomalies.
4. Anomaly Identification: Detected anomalies are identified, and their characteristics, such as size and intensity, are analyzed.

5. Classification: Depending on the nature of anomalies, further classification may be performed based on gradient information or additional sensor data

3.5 Integration with Military Geomagnetic Data

3.5.1 Geo-spatial Data Acquisition

Access to military geomagnetic data is instrumental in our project. We acquire this data from authoritative military sources, ensuring its relevance and compatibility with our analysis. The data's format is tailored to align seamlessly with our analysis requirements, enabling straightforward integration into our workflow.

3.5.2 Data Integration

Geo-spatial analysis software plays a pivotal role in our data integration process. This software facilitates the harmonious merging of military geomagnetic data with our existing datasets. It offers powerful tools for data processing, enabling us to visualize, analyze, and interpret the combined datasets effectively. This integration enhances our analytical capabilities and aligns our project with stringent military standards.

CHAPTER 4: DRONE CONFIGURATION

4.1 Quad-copter Drone Specifications

In this section, we delve into the specifications and characteristics of the quad-copter drone utilized in our project. The quad-copter, a versatile unmanned aerial vehicle (UAV), serves as the primary platform for magnetic field data collection, making its specifications crucial to the project's success.

Physical Characteristics:
The quad-copter boasts a medium-sized frame with dimensions optimized for stability and maneuverability. With a **frame size of approximately 450mm**, it strikes a balance between portability and functionality. It is constructed from lightweight yet durable materials to ensure structural integrity while minimizing weight, allowing for extended flight duration's.

1. **Propulsion System:** The propulsion system is powered by a **12V 5200mAh Li-Po (Lithium Polymer) battery** with a **discharge rate of 40 C** and a **3-cell** configuration. This high-capacity battery provides the necessary energy for sustained flight operations. The quad-copter employs a **3-cell LiPo battery** for efficient power management, ensuring a stable power supply throughout the mission.

2. **Additional Features:** Equipped with telemetry technology, the quad-copter can transmit real-time data to the ground station, enabling remote monitoring and control during flight operations. The inclusion of a camera allows for visual data capture, aiding in the alignment of magnetic field readings with physical locations.

3. **Customization for Project Needs:** While the quad-copter serves as a versatile platform, it has undergone specific customization's to align with the project's objectives. This includes the integration of a high-precision flux-gate-like magnetometer sensor for magnetic field measurements. These modifications enhance the quad-copter's capabilities, enabling it to collect magnetic field data accurately and efficiently.

4.2 Sensor Integration

In this section, we explore the integration of crucial sensors into our quad-copter drone to facilitate magnetic field data collection. The success of our project heavily depends on the accurate and synchronized measurements provided by these sensors.

1. **GPS Sensor:** The GPS sensor serves as the primary means of tracking the drone's precise location during flight operations. It provides latitude, longitude, altitude, and time information. Integrated seamlessly into the drone's architecture, the GPS sensor ensures that the magnetic field measurements are tagged with accurate geographic coordinates.

2. **Magnetometer (Flux-gate Sensor):** A high-precision flux-gate-like magnetometer sensor is integrated into the drone's payload. This specialized sensor enables the measurement of magnetic field intensity. Its orientation is carefully calibrated to align with the drone's flight path, ensuring accurate magnetic field data collection.

3. **Additional Sensors:** Depending on project requirements, additional sensors, such as an inertial measurement unit (IMU) for stability and orientation data, may be integrated for enhanced data accuracy. These sensors work in synergy to provide a comprehensive data-set for magnetic field analysis.

4. **Data Synchronization:** To ensure data synchronization, the sensors are connected to the onboard computer (Raspberry Pi). Data collected by these sensors is timestamped and synchronized, allowing for precise alignment of magnetic field measurements with geographic coordinates.

4.3 Onboard Hardware (Raspberry Pi)

This section delves into the role of the onboard computer, a Raspberry Pi, in controlling the drone's systems and managing data processing during flight operations.

1. **Raspberry Pi Model and Configuration:** The Raspberry Pi serves as the brain of our drone. It is configured to meet the specific demands of the project, offering computational power and versatility. Details regarding the Raspberry Pi model, storage capacity, and connectivity options are included.

2. **Integration with Drone Systems:** The Raspberry Pi is seamlessly integrated with the drone's hardware and sensors. It facilitates real-time data acquisition, preprocessing, and telemetry data transmission. Custom software applications are run on the Raspberry Pi to ensure efficient control and data management during flights.

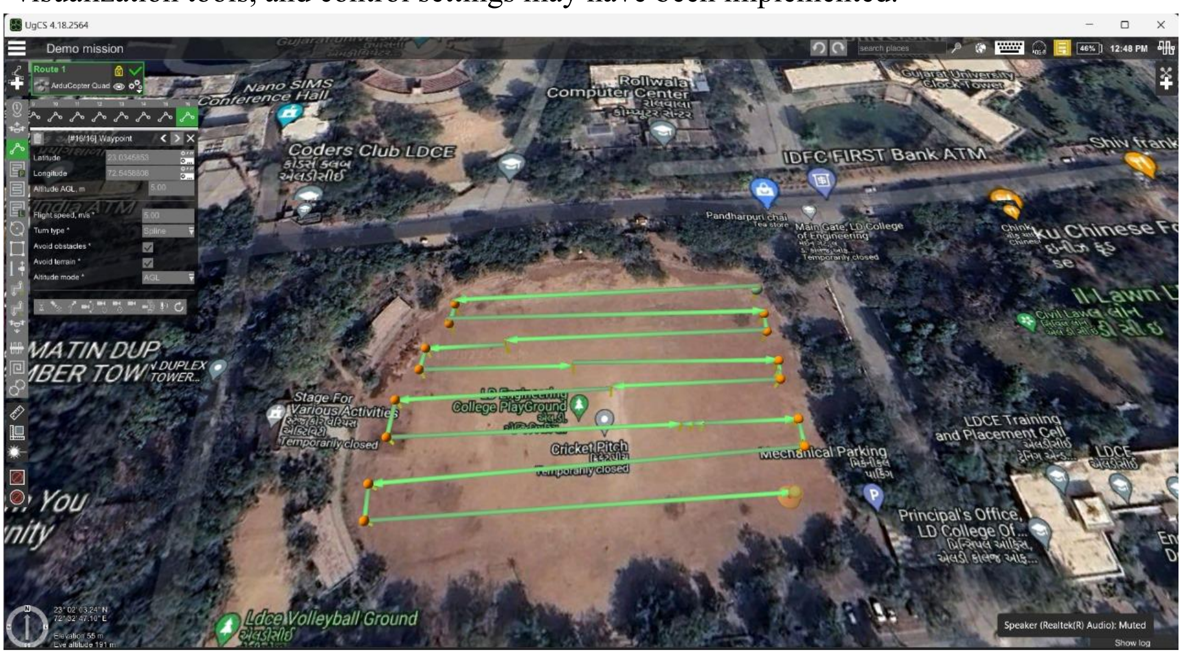
4.4 Flight Control Software (UGCS-like)

In this section, we discuss the flight control software, which plays a pivotal role in planning flight paths, executing missions, and ensuring safe drone operations.

1. **UGCS-like Software Overview:** We employ a UGCS-like software solution, tailored for our project's requirements, to control the drone's flight operations. The software provides an intuitive interface for mission planning, real-time monitoring, and autonomous flight.

2. **Features and Capabilities:** Highlight the key features and capabilities of the flight control software, including GPS waypoint navigation, geo-fencing, and telemetry data visualization. Emphasize how these features enhance mission efficiency and safety.

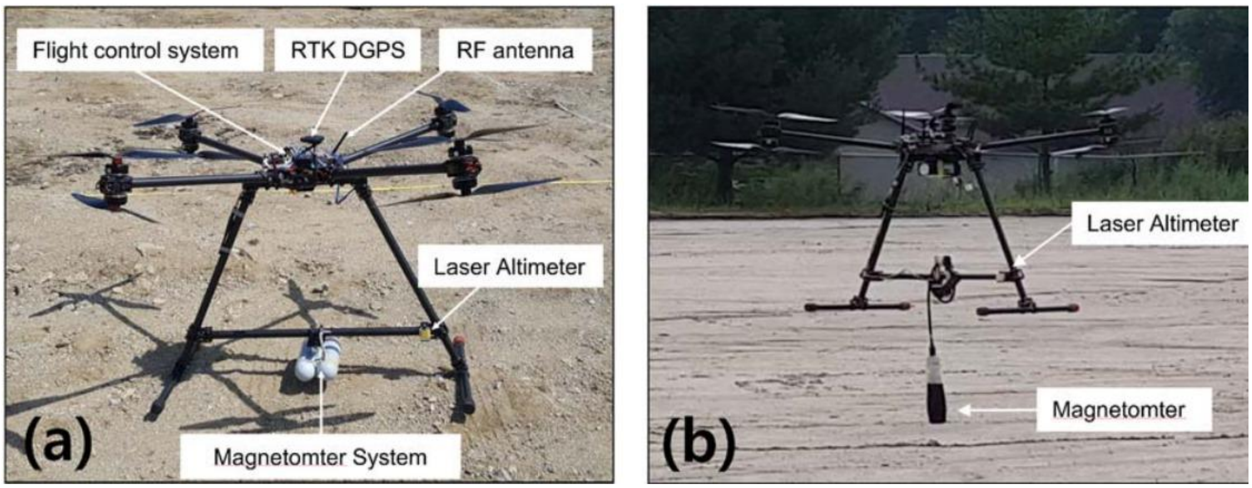
3. **Customization's for Project Needs:** Discuss any customization's or modifications made to the UGCS-like software to adapt it to our specific mission objectives. Custom mission profiles, data visualization tools, and control settings may have been implemented.



CHAPTER 5: DATA ACQUISITION & PROCESSING

5.1 Sensor Data Collection

Data collection from the magnetometer, GPS, and Raspberry Pi camera sensors is a fundamental aspect of capturing information related to magnetic fields, location, and visual data. Here's how data is collected from each of these sensors:



1. **Magnetometer Data Collection:**

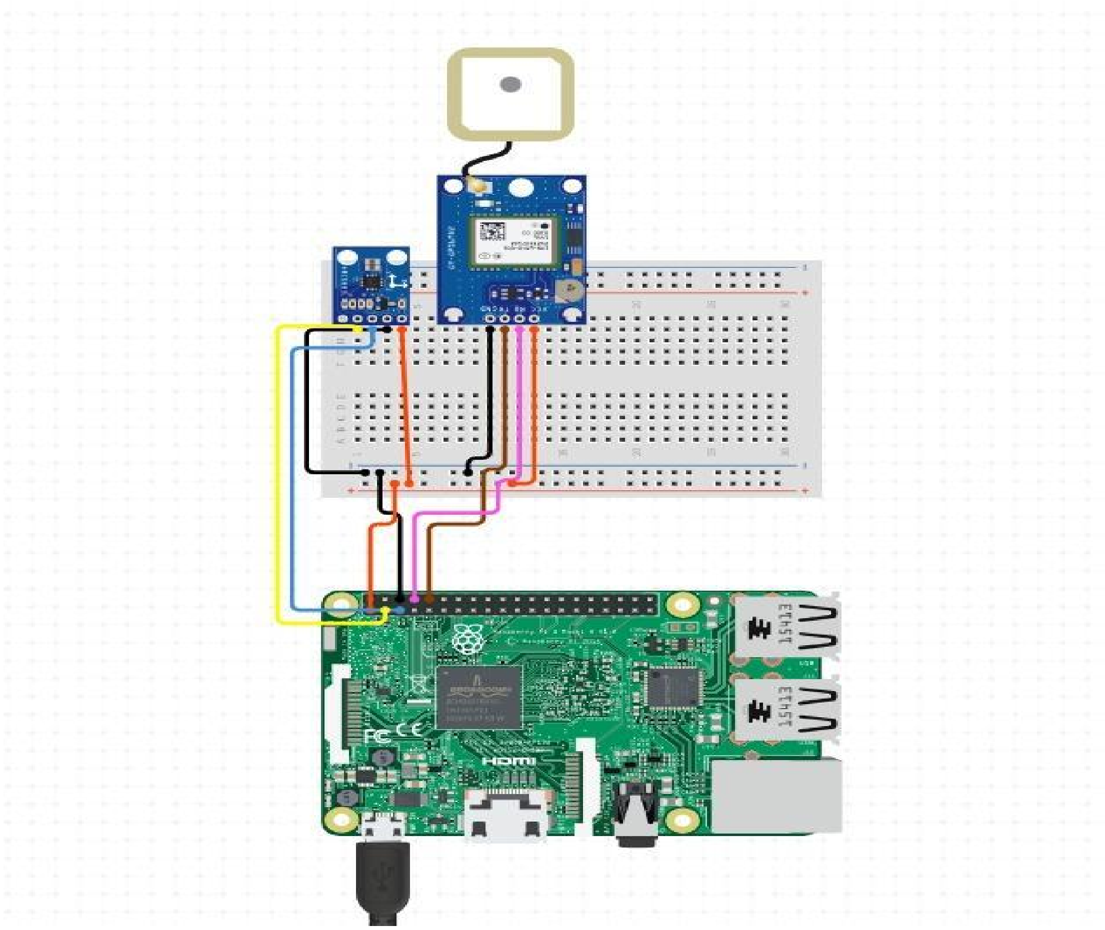
The magnetometer sensor is responsible for measuring magnetic field strength and orientation.
Data from the magnetometer sensor is continuously collected. This data includes information about the magnetic field's magnitude and direction at specific points in time. The magnetometer sensor typically provides real-time data that reflects changes in the Earth's magnetic field as the drone moves.

2. **GPS Data Collection:**

The GPS (Global Positioning System) receiver is used to determine the drone's precise location, altitude, speed, and other relevant geospatial information. The GPS receiver communicates with multiple satellites in orbit to calculate the drone's position and velocity. Data from the GPS receiver is collected with timestamps, providing accurate location and time-related data.

3. **Raspberry Pi Camera Data Collection:**

The Raspberry Pi camera is used to capture images and, potentially, videos during the drone's flight.
Images and videos are recorded based on predefined settings or triggers. For example, images may be captured at regular intervals or in response to specific events. Each image or video frame is treated as a separate data point and is associated with metadata such as file names, timestamps, and file paths.



4. **Timestamp Synchronization:**

To ensure that data from all sensors is synchronized, timestamps are crucial. Timestamps are recorded alongside sensor readings and data points.

Timestamps allow for the correlation of data from different sensors, ensuring that magnetic field measurements, location information, and visual data are all aligned in time.

5. **Data Continuity:**

Data collection is a continuous process throughout the drone's operation. As the drone moves and performs its tasks, sensor data is continuously updated and recorded.

Real-time data is crucial for making immediate decisions during the drone's flight and for ensuring the accuracy of post-flight analysis.

6. **Data Storage and Handling:**

Collected data is stored either onboard the drone or transmitted to a ground station for storage and analysis, depending on your project's setup.

The ground station or onboard computer (e.g., Raspberry Pi) may preprocess, format, and organize the data before it is stored for further processing and analysis.

5.2 Error Handling and Data Integrity

Ensuring data integrity and implementing error handling mechanisms is critical to maintain the accuracy and reliability of the collected sensor data. Here's an overview of how error handling and data integrity are managed:

1. Error Sources:

- **Sensor Inaccuracies:** Sensors, including the magnetometer, GPS, and Raspberry Pi camera, may produce inaccurate readings due to manufacturing tolerances or environmental factors.
- **Environmental Interference:** External magnetic fields, GPS signal loss, or camera lens distortions can introduce errors into the data.
- **Communication Errors:** During data transmission from the drone to the ground station via telemetry, packet loss or data corruption may occur.

2. Error Handling Mechanisms:

- **Calibration:** Sensors are calibrated to correct for systematic errors and biases. Calibration routines are periodically run to ensure accurate measurements.
- **Data Validation:** Collected data is subjected to real-time validation checks to identify outliers or abnormal readings. Data points that fall outside acceptable ranges are flagged.
- **Interpolation:** Missing or corrupted data points may be interpolated using neighboring valid data to fill gaps.
- **Redundancy:** Redundant sensors or measurements may be used to cross-verify data. Inconsistencies trigger alerts for further investigation.
- **Error Logging:** Errors, warnings, and exceptions are logged with timestamps and detailed descriptions for debugging and auditing purposes.

3. Data Integrity:

- **Timestamp Consistency:** Timestamps are carefully synchronized across all sensor data to ensure accurate temporal alignment. Timestamp inconsistencies can lead to misinterpretation of data.
- **Data Quality Reporting:** Any data points that have undergone error correction or validation checks are marked with flags to indicate their reliability. This information is essential for subsequent data analysis.
- **Backup and Redundancy:** Backup copies of collected data may be stored in case of data loss or corruption. Redundant sensors or telemetry channels provide additional layers of data backup.
- **Data Integrity Maintenance:** Data integrity is maintained throughout the data transformation process, including the conversion of raw sensor data into CSV format. Any errors or discrepancies identified during data transformation are addressed to prevent data corruption.
- **Data Compression and Reduction:** Large datasets may be compressed or reduced in granularity to manage storage and processing requirements while minimizing data loss.

By implementing these error handling mechanisms and data integrity practices, this project ensures that the collected sensor data remains accurate and reliable, supporting precise magnetic anomaly detection and other critical analyses outlined in the project's objectives.

5.3 CSV Data Transformation

The transformation of raw sensor data into CSV (Comma-Separated Values) format is a critical step for efficient data analysis and storage. Here's a summary of how CSV data transformation is carried out:

1. **Data Collection:**
   Raw sensor data is continuously collected from various sources, including magnetometers, GPS receivers, and Raspberry Pi cameras. These sensors capture information related to magnetic fields, location, and visual data.

2. **Data Preprocessing:**
   Before conversion, data preprocessing steps may be applied to ensure data quality. This can include calibration of magnetometer data to correct sensor biases and ensure accuracy.

3. **Data Formatting:** Each type of sensor data is structured and formatted appropriately for CSV conversion. Magnetometer data includes timestamps, magnetic field strength, orientation, and other relevant parameters. GPS data consists of timestamps, latitude, longitude, altitude, speed, and satellite signal quality. Camera data involves metadata such as file names, timestamps, and file paths.

4. **CSV File Creation & Structure:** Separate CSV files are created for each type of sensor data (magnetometer, GPS, camera) or combined into a single CSV file depending on your project's requirements. A consistent structure is defined for the CSV file(s). Each row represents a single data point with columns corresponding to different sensor measurements or metadata fields.

5. **Data Export:** The formatted sensor data is exported and written into the respective CSV file(s) using programming languages or data processing software.

6. **Timestamp Consistency:** Timestamps across all sensor data are cross-verified to ensure precise alignment, which is crucial for data synchronization during analysis.

7. **Data Compression and Reduction:** To manage large datasets efficiently, consider data reduction techniques. You may aggregate or summarize readings over time intervals, reducing granularity. Implement data compression if necessary, using methods like ZIP, GZIP, or binary encoding. Ensure data compression maintains data quality.

8. **Error Handling:** Error handling mechanisms are in place to address issues that may occur during data transformation, such as missing sensor readings or file I/O errors.

9. **Data Storage:** The generated CSV file(s) are saved in a designated storage location, either on the drone's onboard storage or on an external data storage device.

10. **Data Continuity:** Continuous data transformation ensures that new sensor data is regularly added to the CSV file(s) as it becomes available during the drone's operation.

By following this CSV data transformation process, we can efficiently convert raw sensor data into a structured format that is suitable for analysis, archival, and further processing in this project. This structured data enables accurate magnetic anomaly detection and other analyses.

5.4 Telemetry Data Transmission Process

Telemetry data transmission is a crucial aspect of sending sensor data from the drone to the ground station for further analysis and processing. Here's a detailed explanation of the telemetry data transmission process:

1. **Data Source:** Sensor data from various sources, including the magnetometer, GPS, and Raspberry Pi camera, serves as the primary data source.

2. **Data Collection and Aggregation:** Collected data is aggregated and organized into a structured format. This ensures that the data is in a suitable form for transmission and analysis.

3. **Data Preprocessing:** Data preprocessing may involve calibration, error correction, and validation to enhance data quality and accuracy. This step is crucial before data transmission.

4. **Telemetry Radio Setup:** Telemetry radios are integrated into both the drone and the ground station. These radios enable wireless communication between the two endpoints.

5. **Data Serialization:** The structured sensor data is serialized into a format suitable for transmission via the telemetry radio. Serialization transforms the data into a stream of bytes that can be transmitted.

6. **Telemetry Transmission:** The serialized data is transmitted over the telemetry radio using a designated communication protocol and frequency (e.g., 433MHz). The telemetry radio on the drone transmits the data, while the ground station's telemetry radio receives it.

7. **Error Handling and Correction:** During transmission, data packets may experience issues such as packet loss or corruption due to interference or signal degradation. Error detection and correction mechanisms are employed to identify and recover from transmission errors. This ensures data integrity.

8. **Data Reception:** The telemetry radio on the ground station receives the transmitted data. The radio may include a receiver antenna to capture the signal effectively.

9. **Data Deserialization:** Upon reception, the serialized data is deserialized, converting it back into a structured format for further processing and analysis.

10. **Data Storage and Analysis:** The received data is stored in a designated storage location on the ground station, such as a database or file system. Analysis tools and algorithms are applied to the data to perform tasks like magnetic anomaly detection and object classification, as outlined in your project's objectives.

11. **Real-Time Feedback (Optional):** In some cases, real-time feedback or control signals may be transmitted from the ground station to the drone via telemetry. This can include adjustments to the drone's flight path or sensor settings.

12. **Continuous Data Flow:** The telemetry data transmission process is continuous and real-time, ensuring that new sensor data from the drone is continually sent to the ground station for immediate analysis and decision-making.

By following this telemetry data transmission process, this project maintains a seamless flow of sensor data from the drone to the ground station, enabling the analysis and detection of magnetic anomalies and other critical tasks. The integration of error handling mechanisms ensures that data integrity is preserved throughout the transmission.

CHAPTER 6: SELF-MAGNETIC FIELD COMPENSATION

6.1 Introduction to Self-Magnetic Field Compensation

Why is compensation necessary ?

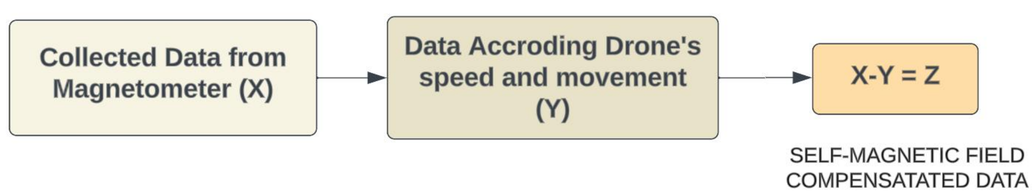
Magnetic field compensation is essential to ensure the **accuracy, reliability,** and **performance** of systems and devices that rely on magnetic sensors.
It helps correct for interference and ensures that measurements reflect the true external magnetic field, which is critical in a wide range of applications, from navigation and geophysics to scientific research and technology development.

6.2 Algorithms for Self-Magnetic Field Estimation

1. **Initialization:** Initialize variables to store the **Measured magnetic field** (B_raw) (X) and the compensated magnetic field (B_comp) (Z). Set a sampling rate for data acquisition.

2. **Data Acquisition Loop:** Continuously collect magnetic field measurements from the sensor at the specified sampling rate (X).

3. **Orientation Estimation:** Obtain the orientation of the sensor (roll, pitch, yaw) from an Inertial Measurement Unit (IMU) or other orientation (Gyroscope) sensors (Y).



4. **Magnetic Field Model:** Calculate the expected magnetic field at the sensor's location based on the Earth's magnetic field model (e.g., IGRF) and the current geographic position and orientation of the sensor. The expected magnetic field (B_expected) is a vector representing the magnetic field's strength and direction at the sensor's location.

5. **Compensation Calculation:** For each **measured magnetic field component** (Bx_raw, By_raw, Bz_raw), calculate the compensated component(Z) (Bx_comp, By_comp, Bz_comp) by subtracting the expected component: **Bx_comp = Bx_raw - Bx_self, By_comp = By_raw -**

By_self, Bz_comp = Bz_raw - Bz_self. These calculations remove the contribution of the Drone's magnetic field from the measured data.

6. **Combine Components:** Combine the compensated magnetic field components (Bx_comp, By_comp, Bz_comp) to obtain the compensated magnetic field vector = [Bx_comp, By_comp, Bz_comp]

7. **Data Logging/Usage:** Log or use the compensated magnetic field vector (B_comp) for further processing, analysis, or navigation. Repeat: Continuously repeat the data acquisition and compensation process to maintain accurate measurements, considering changes in sensor orientation and position.

6.3 Implementation Details

Describe the practical implementation of the selected self-magnetic field estimation algorithm. Include code snippets or pseudocode to illustrate the key steps. Mention any challenges encountered during implementation and how they were addressed.

6.4 Calibration and Testing

Explain the calibration process to fine-tune the compensation algorithm. Describe the test setup and procedures used to evaluate the accuracy of self-magnetic field compensation. Present results and comparisons before and after compensation to demonstrate its effectiveness.

6.5 Limitations and Future Improvements

Acknowledge any limitations or constraints associated with the self-magnetic field compensation method. Suggest potential areas for improvement or further research to enhance the compensation process. Address any remaining challenges or uncertainties in the compensation technique.

CHAPTER 7: ANOMALY DETECTION & ANALYSIS

7.1 Introduction to Anomaly Detection

1. **The Significance of Anomaly Detection:** Anomaly detection plays a pivotal role in our drone-based magnetic sensing system. It serves as the core mechanism for identifying metallic objects by distinguishing magnetic anomalies from the Earth's ambient magnetic field. The significance of anomaly detection lies in its capability to enhance military applications, such as threat detection and security measures.

2. **Project Objectives:** Our project's primary objectives revolve around the precise identification and classification of magnetic anomalies. We aim to develop a robust system that can accurately detect and categorize metallic objects in real-time, thus contributing to improved situational awareness and operational effectiveness.

7.2 Data Preprocessing

1. **Data Acquisition:** To achieve accurate anomaly detection, we employ a set of sensors on our drone, including magnetometers and GPS units. These sensors continuously collect data while the drone is in flight, providing essential inputs for the detection system.

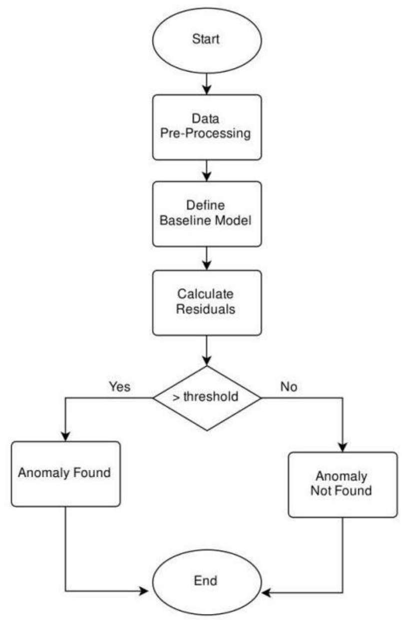
2. **Data Preprocessing Steps:** Before analyzing the collected data, a series of preprocessing steps are essential. These steps involve data calibration, coordinate transformation, and error handling. Ensuring data compatibility and accuracy is paramount to the success of our anomaly detection system.

7.3 Anomaly Detection Algorithms

1. **Data-set: Earth Magnetic Anomaly Grid (EMAG) 2**
   EMAG2 (Earth Magnetic Anomaly Grid 2-arc-minute resolution) is compiled from satellite, ship, and airborne magnetic measurements. Magnetic anomalies result from geologic features enhancing or depressing the local magnetic field. These maps increase knowledge of subsurface structure and composition of the Earth's crust. Global magnetic anomaly grids are used for resource exploration, navigation where GPS is unavailable (submarine, directional drilling, etc.), and studying the evolution of the lithosphere.

2. **Gridded Magnetic Algorithm:** The Gridded Magnetic Algorithm is a fundamental component of our detection system. It divides the survey area into a grid of cells and calculates the magnetic

field strength for each cell. By comparing these values with expected field strengths derived from open-source geomagnetic data, we can identify deviations indicative of magnetic anomalies.



3. **Gradient-Based Anomaly Detection Algorithm:** Working in tandem with the Gridded Magnetic Algorithm, the Gradient-Based Anomaly Detection Algorithm focuses on the spatial gradients of magnetic field strength. This approach assesses the changes in magnetic field intensity across the survey area, allowing us to pinpoint areas with significant variations as potential magnetic anomalies.

7.4 Data Analysis and Interpretation

1. **Comparative Analysis:** A crucial step in anomaly detection is the comparison of measured magnetic field data with open-source geomagnetic data. By aligning these datasets, we can identify areas where measured values deviate significantly from expected values, indicating the presence of magnetic anomalies.

2. **Anomaly Score Calculation:** To quantify the detected anomalies, we calculate anomaly scores based on the differences between measured and expected magnetic field values. These scores provide a means of prioritizing anomalies based on their magnitude and significance.

3. **Threshold:** Setting a threshold for anomaly scores is a critical decision. Scores exceeding this threshold are considered anomalies, allowing us to filter out false positives and focus on areas with the highest likelihood of containing metallic objects.

4. **Visual Representation:** To aid in data interpretation, we employ various visualization techniques, including heat maps and contour plots. These graphical representations provide a clear visual understanding of magnetic anomalies across the survey area.

7.5 Classification of Anomalies

1. **Anomaly Categorization:** Detected anomalies are categorized based on their characteristics, such as size, shape, and intensity. This categorization assists in understanding the nature of the anomalies and their potential implications.

2. **Potential Threat Assessment:** In military applications, assessing the potential threat level associated with each detected anomaly is critical. By considering anomaly characteristics and other contextual information, we can prioritize responses and allocate resources effectively.

7.6 Performance Evaluation

1. **Metrics for Evaluation:** Evaluating the performance of our anomaly detection system is vital. We employ metrics such as accuracy, precision, recall, and F1-score to assess its effectiveness in identifying and classifying anomalies.

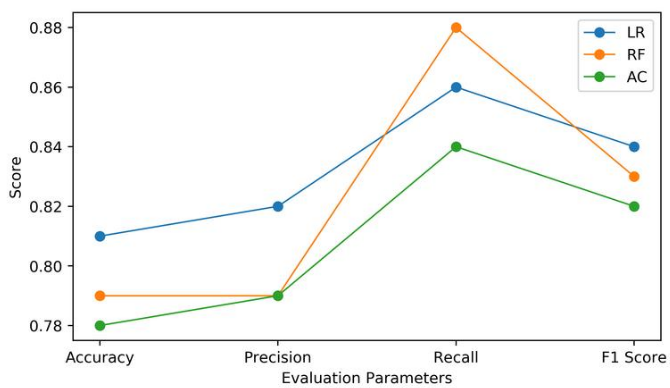
2. **Case Studies:** Real-world case studies illustrate the practical application of our system. These scenarios showcase instances where the system successfully detected and classified anomalies, providing insights into its operational capabilities.

CHAPTER 8: PERFORMANCE EVALUTION & VALIDATION

8.1 Performance Metrics

8.1.1 Accuracy : Accuracy measures the system's ability to correctly identify both true anomalies and non-anomalies. Our analysis provides a quantitative assessment of accuracy under different scenarios.

8.1.2 Precision : Precision quantifies the system's capability to correctly identify true anomalies among the detected anomalies. We delve into precision's significance in military applications.



8.1.3 Recall : Recall assesses the system's ability to identify all true anomalies, demonstrating its sensitivity to potential threats. We provide a detailed examination of recall metrics across various test cases.

8.1.4 F1-Score : The F1-Score combines precision and recall, offering a balanced evaluation of overall system performance. We analyze how this metric reflects the system's robustness and reliability.

8.2 Test Scenarios (Validation) and Case Studies

Our performance evaluation includes **diverse test scenarios** and real-world case studies to validate the system's adaptability and reliability:

8.2.1 Urban Environments: We scrutinize the system's performance in urban settings, where metallic objects can be concealed within complex structures, presenting unique detection challenges.

8.2.2 Rural and Remote Areas: Testing in rural and remote areas assesses the system's effectiveness in identifying anomalies in less populated regions, where military operations may differ significantly.

8.2.3 Dynamic Scenarios: Simulated dynamic scenarios, where objects are in motion, challenge the system's real-time detection capabilities. We explore how the system adapts to rapidly changing conditions.

8.3 Discussion

In this section, we engage in a comprehensive discussion, dissecting the implications of performance evaluation results: Strengths and Weaknesses We analyze the system's strengths and weaknesses, considering factors such as **environmental conditions, object characteristics** and **operational constraints**.

8.4 Recommendations and Future Directions

8.4.1 Recommendations for Enhancement : Building on our findings, we propose recommendations for system enhancements. These suggestions aim to further improve accuracy, adaptability, and real-world applicability.
8.4.2 Exploring Future Avenues : we explore potential future directions, including advanced sensor integration, machine learning algorithms, scalability for broader deployment, and collaborative research opportunities with institutions and organizations.