

Master Thesis

**Autonomous Vision-based
Safe Proximity Operation of
a Future Mars Rotorcraft**

Autumn Term 2024

Contents

Abstract	iii
1 Evaluation	1
1.1 SFM Insufficiencies	1
1.2 LSD Analysis	1
1.3 Experimental Setup	3
1.3.1 Simulated Terrain	4
1.3.2 Drone Spawn	4
1.3.3 Depth Source	10
1.3.4 Success Conditions	10
1.3.5 Visual Analysis	12
1.4 Test Flights	13
1.4.1 Arroyo - Randomized Waypoints	13
1.4.2 Arroyo - Randomized Takeoff and Waypoints	15
1.4.3 Rough Map - Mission Covering Platforms	17
1.4.4 Rough Map - Random Waypoints	19
1.4.5 Rough Map - Random WPs with Larger Search Radius	20
1.4.6 Arroyo - Randomized Takeoff and Mission with SFM	21
1.5 Theoretical Edge Cases	22
1.5.1 Arrival on Mars	23
1.5.2 Flying on Large Scale Inclined Terrain	24
Bibliography	25

List of Acronyms

- **UAV:** Unmanned Aerial Vehicle
- **SFM:** Structure From Motion
- **LSD:** Landing Site Detection
- **LS:** Landing Site
- **BA:** Bundle Adjustment
- **DEM:** Dense Elevation Map
- **OMG:** Optimal Mixture of Gaussian
- **LOD:** Level Of Detail
- **HiRISE:** High Resolution Imaging Science Experiment
(High Resolution Satellite Imagery on the Mars Reconnaissance Orbiter (MRO))
- **LRF:** Laser Range Finder
- **GT:** Ground Truth
- **LSM:** Landing Site Manager
- **FSM:** Finite State Machine
- **BT:** Behavior Tree

Abstract

An autonomous rotorcraft literally stands or falls on its reliable landing capabilities. This procedure cannot fail even once when that same rotorcraft is on Mars. The LORNA (Long Range Navigation) project tackles this problem by introducing a Landing Site Detection (LSD) mechanism that aggregates Structure From Motion (SFM) point clouds into a multi-resolution elevation map and performs landing site segmentation on the collected depth information. In this master's thesis we incorporated this landing site detection pipeline into an autonomy framework. We implemented a behavior tree based landing mechanism to safely and efficiently select, verify and discard detected landing sites. Furthermore, the pipeline was enhanced using a stereo camera depth input alternative to SFM for lower altitudes to remove the necessity of lateral motion to perceive depth. The software was tested extensively in a gazebo simulation on different synthetic as well as recorded environments, and different behaviors were considered and analyzed throughout various Monte Carlo iterations. The contributions in this work aim to enable future Mars rotorcrafts to autonomously and reliably land at safe locations, thus enabling a more daring aerial exploration of the red planet.

Chapter 1

Evaluation

Before analyzing the work done in this thesis, the depth acquisition pipeline, consisting of the SFM and LSD algorithm are discussed.

1.1 SFM Insufficiencies

SFM is part of the LORNA pipeline and proved to be a valid option for the tackled endeavor. Prior to this work however, it was never tested extensively, especially at high altitudes (100 m).

Though very well performing when initialized successfully at low to mid-altitudes, SFM often had issues during startup and showed frequent insufficiencies when the drone rotated or when switching the key frames used for the stereo at high altitudes. Unfortunately, a lack of time prevented me from diving into these issues. Nevertheless, the shortcomings of the current standing are laid out to the best of my current knowledge in the following to hopefully be resolved in future work.

First, SFM showed a substantial lack of robustness when being initialized. If the drone was at all rotating during initialization, SFM would either crash or not start up at all. fig. 1.1 shows an image of a corrupted DEM due to bad SFM information. After initialization SFM showed to still be prone to produce corrupted data when rotating between mission waypoints or landing site attempts. Bad SFM results are fed into LSD's elevation map and are retained until these points are overruled. Therefore, a single corrupted SFM point cloud lastingly impacts the DEM and thus LSD's capability of detecting high quality landing sites.

Another pressing issue is SFM's manner of handling motion at high altitudes: As described in ??, SFM stays at the same reference key frame for stereo depth creation until that key frame's overlap with the new image is too small, and the key frame is switched out. In practice this can be seen as jumps in the LSD algorithm, where the new point cloud's center is at a new location far enough from the previous center, that a significant shift of the rolling buffer has to be performed and a large part of the DEM has to be filled again. During this time, no landing sites are detected.

This phenomenon can be seen in fig. 1.2.

The issue with large map shifts is the removal of most of the DEM's information which leads to the delay of landing site detection on most of the map.

1.2 LSD Analysis

Given high quality depth clouds, the LSD algorithm is able to accurately detect valid landing sites without fail.

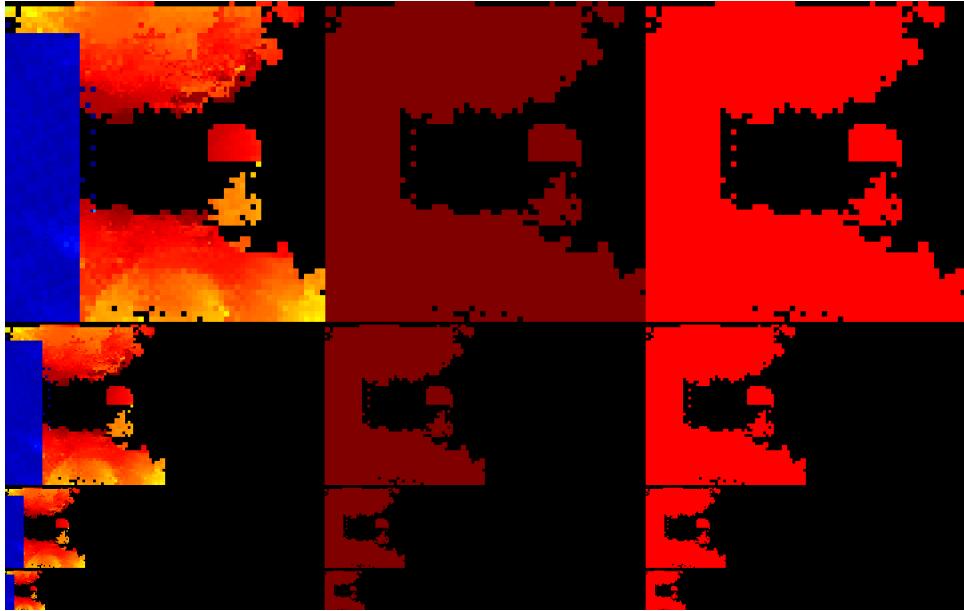


Figure 1.1: One example of the LSD output when supplied with suboptimally performing SFM

LSD's consideration of the same terrain at different resolutions leads to a very consistent elevation map. However, when flying at high altitudes where the image footprint is big, this same characteristic prevents the usage of most of the camera image as only the centermost area coinciding with the other layers of the image is used. This is shown in fig. 1.3.

Due to a fixed number of layers, the image points detected at high altitudes have a pixel footprint which exceeds that of a cell from the coarsest layer. Therefore, the point cloud input to LSD is sparse and leaves many cells empty. Empty cells prevent the detection of landing sites in the neighborhood. The smaller the coarsest layer's cell footprints, the stronger the effect. fig. 1.4 shows the LSD DEM before convergence when using 2 layers at 100 m altitude.

The lowest resolution layer has a fixed resolution of 0.05 m / cell. Considering the 4-fold division of a cell when moving to a higher resolution layer, the resolution at the top level is 0.2 m / cell. On the other hand, at 100 m altitude with the camera parameters introduced in ?? the tracker camera's pixel footprint is 0.363 m/px.

After a while the map is filled with further measurements as shown in fig. 1.5.

However, due to the map movement mentioned in section 1.1, most of the DEM is erased before the DEM converges sufficiently.

This is shown in fig. 1.6. In practice only very few landing sites are detected with these parameters.

A remedy for this is the usage of more layers, resulting in a decreased resolution at the coarsest layer. This way, the discrepancy of the footprints of the incoming points and the cells available is not as big and as a result the DEM is less sparse. It has to be noted however, that using more layers leads to more computational overhead. An example LSD image shortly after initialization with 4 layers is shown in fig. 1.7.

Note that a higher number of layers leads to a stronger pooling effect at the highest resolution layers. In other words, the sparsity of the DEM when using LSD with fewer layers is counteracted with the enhanced pooling of further layers leading to a high resolution layer filled with the same coarse information present at lower

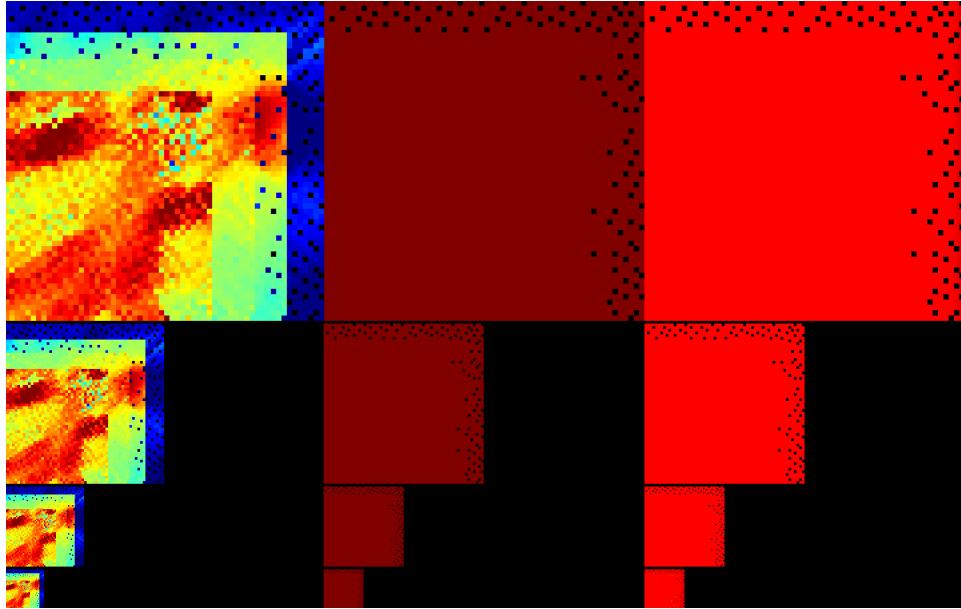


Figure 1.2: Intermediate LSD state after map movement



Figure 1.3: Comparison of the tracker camera image and the region of interest used by LSD

layers. Due to the incoming point cloud’s large point footprint, there is no higher resolution information to be had. Therefore, resolving the sparse maps with coarse information does not denote a loss of information. At high altitudes we want to find areas with promising landing sites. These don’t have to be perfect landing sites themselves yet and serve more as a signifier for later refinement. Thus, using lower resolution information is perfectly nominal.

A more detailed analysis of LSD with various numbers of layers can be found in ??.

1.3 Experimental Setup

The pipeline was tested by repeatedly flying a mission with randomized initial conditions. On each setup 100 flights were performed where each flight was given a maximum of 10 minutes before the next iteration commenced.

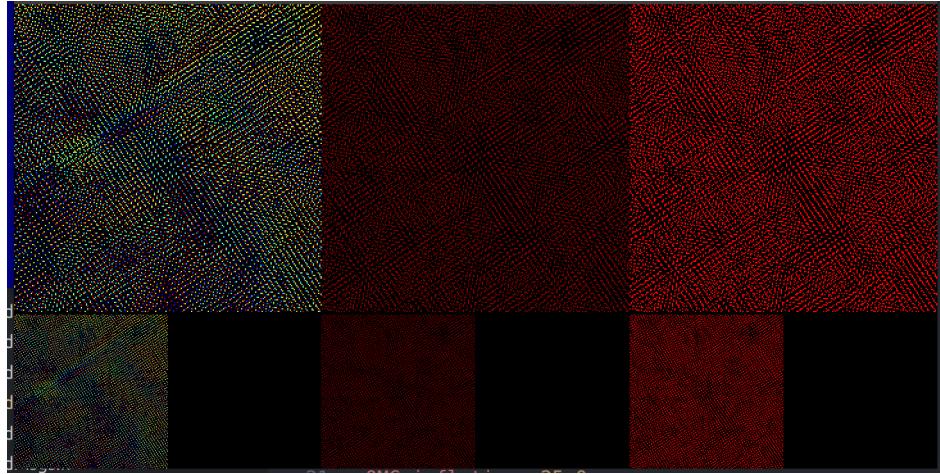


Figure 1.4: LSD DEM at 100 m right after initialization with only 2 layers

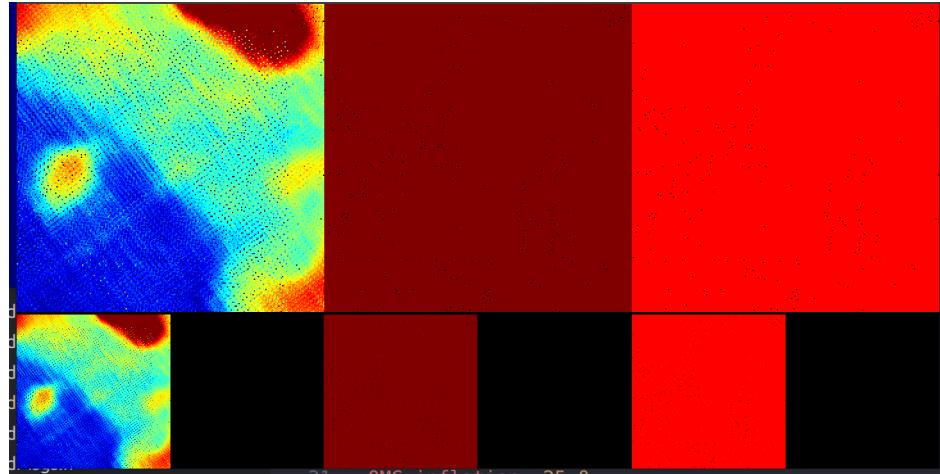


Figure 1.5: DEM at 100 m with 2 layers after some conversion time

1.3.1 Simulated Terrain

The performed experiments were flown on the following two maps:

- Arroyo Map - Map from the Arroyo Seco area outside the East entrance of the Jet Propulsion Laboratory. Predominantly used map during development
- Rough Test Map - A control environment designed to prevent LSD from detecting any landing site unless a landing platform is specifically spawned. It was created using blender and applying white noise perturbations to the elevation of a plane.

1.3.2 Drone Spawn

The drone was either spawned repeatedly from a default location on the ground (The start location from when the actual fields tests were performed) or from a random location. For a simplicity way of avoiding terrain collisions, the drone was spawned on a randomly positioned disk at 40 m altitude. The start disk's size

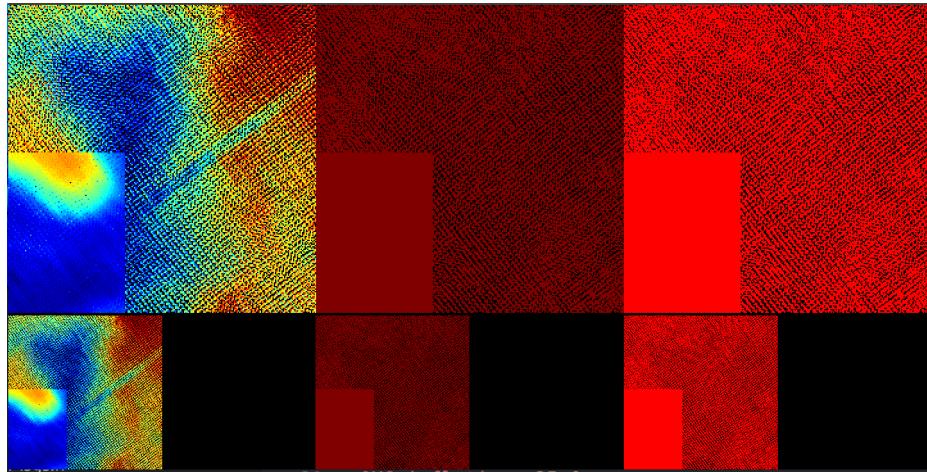


Figure 1.6: DEM at 100 m with 2 layers after map movement

was only 0.5 m in diameter which prevented it from being considered too good of a landing site by LSD. This is important because the platform implicitly gains quality due to the fact, that it is located higher up than the terrain, leading to a lower distance to the drone when flying at mission altitude.

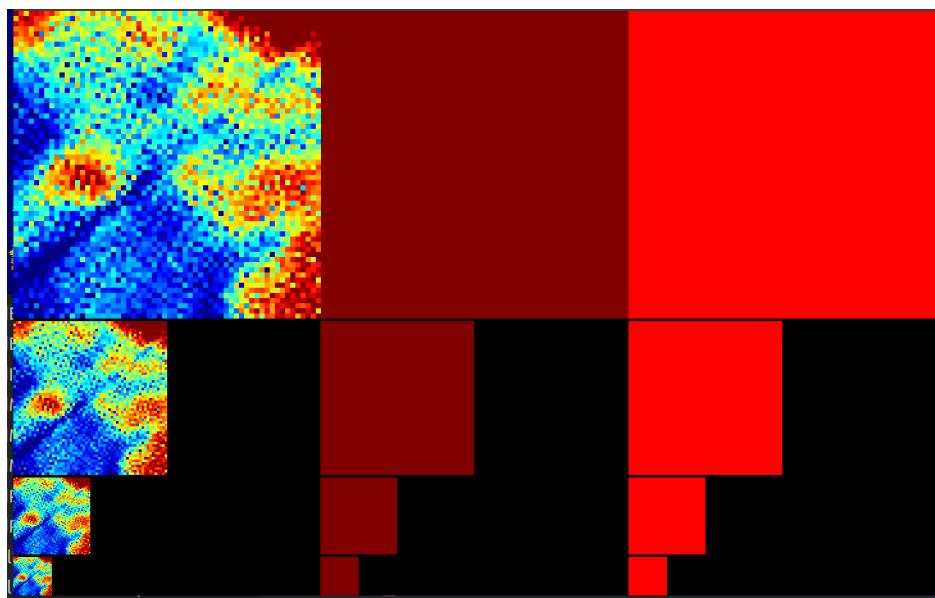


Figure 1.7: LSD DEM at 100 m with 4 layers



Figure 1.8: Map of the Arroyo Seco area outside the Jet Propulsion Laboratory



Figure 1.9: Close Up of the Arroyo Map

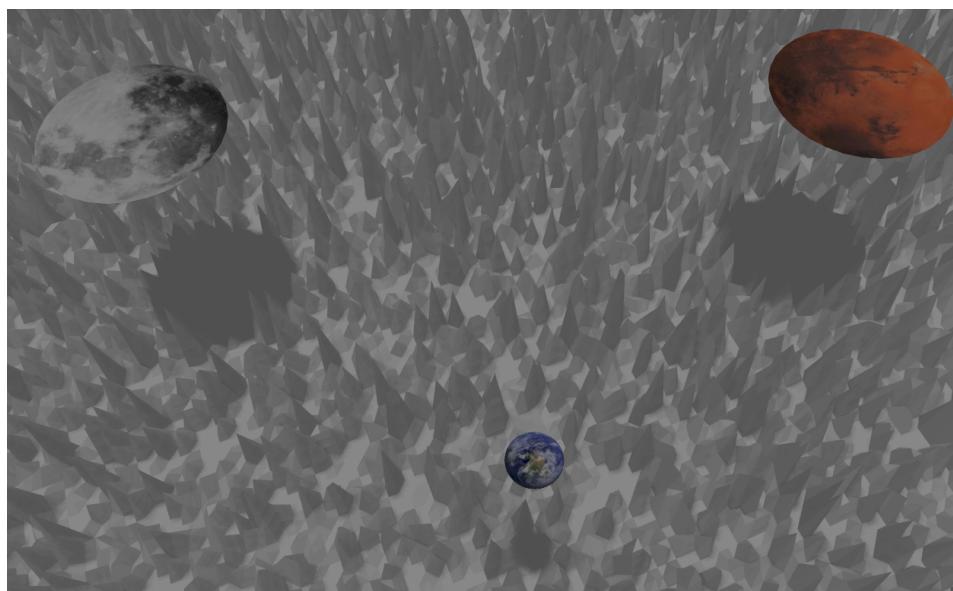


Figure 1.10: Synthetically created map with no landing sites apart from inserted landing platforms.

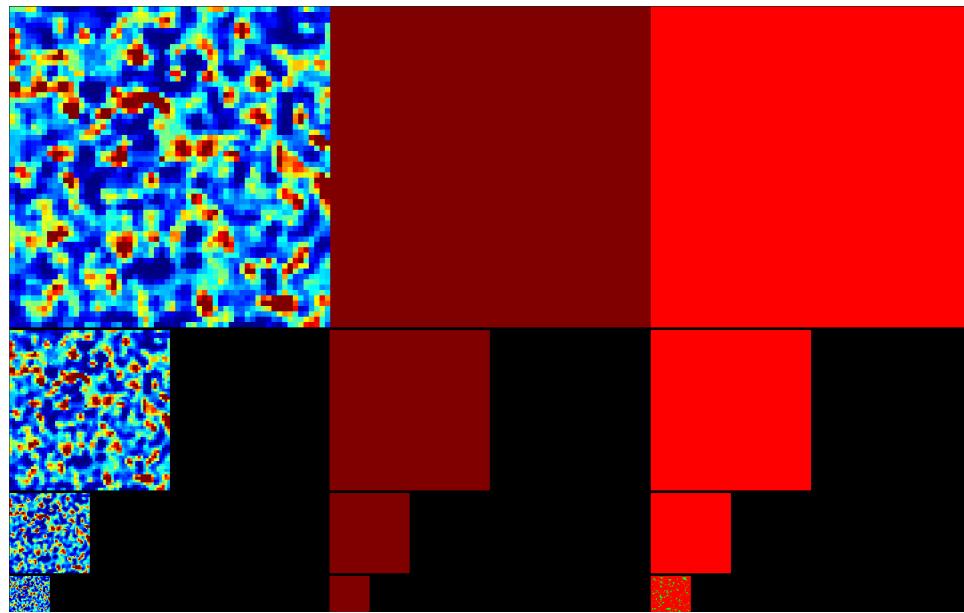


Figure 1.11: LSD debug output shown of the plain rough environment

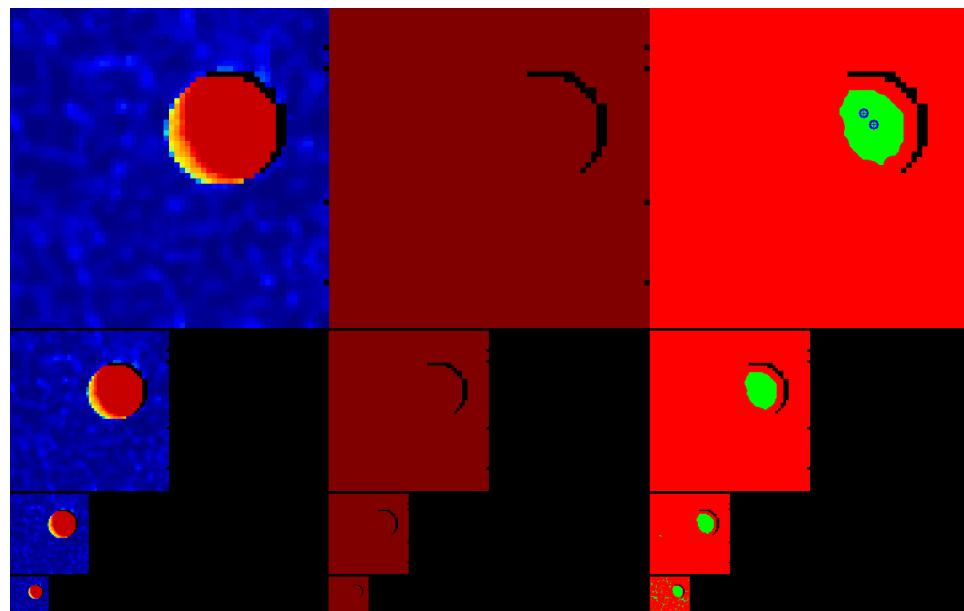


Figure 1.12: LSD debug image of the rough control map with spawned landing platforms



Figure 1.13: Arroyo Map with Fixed Start Position



Figure 1.14: Arroyo map with randomly positioned spawn platform

1.3.3 Depth Source

As mentioned in section 1.1, at the time of this work SFM was very fragile as an individual module. Because of this and to evaluate the landing pipeline as opposed to the depth generation module, ground truth depth was used above the verification altitude. For sake of completeness however, an SFM run is shown in the end as well. Regardless of whether ground truth or SFM was used, the verification at low altitudes was always performed using the stereo camera depth node.

Note that at the rough map introduced in section 1.3.1, there is no texture projected onto the terrain. Therefore, on this map ground truth was used exclusively.

1.3.4 Success Conditions

To determine whether a flight was successful or not, two main metrics were considered. First, whether the landing action in the autonomy was initiated (this happens only after the landing site selection and verification were both successful). Secondly, for each flight a rosbag was recorded. To infer the safety of the rotorcraft, the bag was analyzed to check whether either the roll or pitch value exceeded the crash threshold. In practice, a threshold of 1.2 radians or shortly below 70° proved to be an accurate decision boundary to detect a drone crash.

Home Landings

Landing at the home position defines the behavior when the drone does not navigate towards a landing site but instead uses the stored takeoff coordinates to navigate to the spawn location to land. This happens when no landing sites exist to be chosen. This occurs in two scenarios:

- Few landing sites were detected yet failed verification and were therefore banned. Thereafter, no landing sites remained.
- No landing sites were detected in the first place.

This can happen because of two reasons:

- The overflowed terrain simply does not have a single landing site of decent quality. (see the rough map introduced in section 1.3)
- The landing site detection algorithm failed to detect landing sites.

In both scenarios, going home is the desired behavior. However, if LSD does not detect landing sites where good candidates should be found, the run cannot be counted as a success regardless of whether the drone landed safely after taking off. For instance, looking at the Arroyo map shown in fig. 1.9 and running numerous simulated flights on the terrain, it is clear that sufficient landing sites should be found on this map. Therefore, landing at home when flying on the Arroyo map indicates a landing site pipeline issue.

Off Board Mode connection Issues

Occasionally connection failures between the PX4 flight controller and the autonomy occurred, leading to the deactivation of the off board mode and therefore the loss of control of the autonomy over the rotorcraft. These issues arose most likely because the MAVROS connection in between failed to send a necessary repeated heartbeat and thus the connection was intercepted.

Self-evidently, this did not result in a guaranteed successful landing and was not counted as such. However, as these connection issues did not occur due to insufficiencies in the pipeline presented in this work, they were not considered failures of the pipeline either.

Therefore, to conclude the possible success states:

- Successful: The drone initiated landing and did not fall over throughout the whole flight.
- Connection loss: The autonomy lost the connection to the flight controller and therefore no information can be gathered about this flight and the landing behavior's performance.
- Crash: Either the roll or pitch angle of the drone exceeded the predetermined threshold of 70 degrees. This is a definite failure of the pipeline.
- Home landing: The drone did not settle at a perceived landing site and returned to the home position instead. On a map with sufficient landing opportunities this indicates a failure. When actually not traversing terrain with valid landing sites as was often the case for the rough terrain shown in section 1.4.4, landing home is the desired behavior.

1.3.5 Visual Analysis

To further analyze the randomized flights in a bit more detail, visual landing attempt projections are used. Such an analysis image is shown in fig. 1.15.

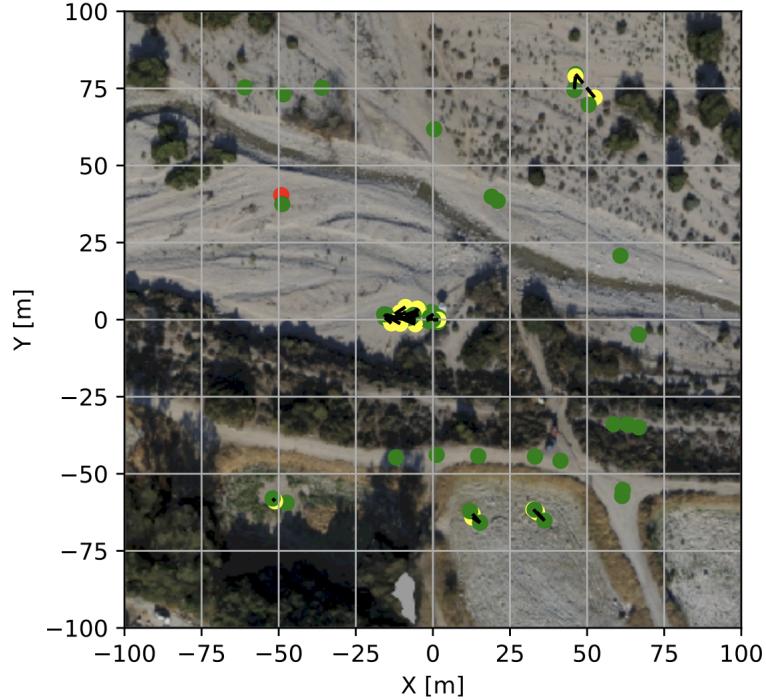


Figure 1.15: Landing Attempt dummy image - Green: successful landing, Yellow: verification failure, Blue: landing at home position

The green points indicate successful verifications which lead to the initiation of the landing action shortly after. (If no rotation above a failure threshold was detected, this is considered a successful landing.)

The yellow points are landing attempts, where a chosen landing site was not verified and thus banned from further consideration. It is crucial to note that not being able to verify a landing site is no issue at all. Landing sites detected at high altitudes merely provide a preliminary indication of potential landing zones. It is the subsequent phase, responsible for verifying these sites, that yields the refined final landing site knowledge used for landing. So selecting a landing site at high altitude, not being able to verify it and subsequently choosing a close by landing site might even be called the most promising chain of actions in the pursuit of autonomous landing.

Blue points indicate successful landings achieved through the trigger of the landing-at-home action. As previously mentioned, When flying on a map with obvious landing opportunities, triggering the landing-at-home action indicates an issue with the landing site detection mechanism.

Lastly, red dots indicate landing sites which were detected during a flight which was disrupted by a connection issue.

In the case of multiple attempts at verifying a landing site, connection lines are drawn between the failed attempts and the final landing indicating which subsequent sites were chosen.

It has to be noted that these plots were generated using non-orthographic back-

ground images and the actual landings took place at locations slightly closer to the image center.

As the created points are rather large, hereafter is the empty background image for reference:



Figure 1.16: Non-orthographic Arroyo background image for visual evaluation of the test flights

1.4 Test Flights

The following tests were performed. Each test consisted of 100 flights simulated in Gazebo.

1.4.1 Arroyo - Randomized Waypoints

When starting 100 times from the fixed position indicated in fig. 1.13 and flying to random mission waypoints at 100 m altitude in a 70x70m vicinity on the Arroyo map, the following results were achieved:

The landing attempt numerics are shown here:

Numeric Discussion

table 1.1 shows the numeric outcome of the flights. 7 timeouts occurred but each performed flight by the autonomy was a success, landing safely and controlled. No

Table 1.1: Results with fixed takeoff and random waypoint

# Flights	# Successes	# Con. Loss	# Crashes	# Home Landing
100	93	7	0	0

Table 1.2: The outcomes of the flights performed. Con. Loss stands for connection loss of the off board mode.

Table 1.3: Landing attempts with fixed takeoff and random waypoint

# Flights	# Landing on first attempt	# 2 attempts	# 3 attempts
93	58	33	2

home landings were necessary which, as described above, indicates a very robust LSD performance. A high number of flights where two landing site verification attempts were performed is also well within acceptable boundaries because the first landing site might as well be used as an indicator to draw the drone closer to an area where high quality sites can be detected using the stereo camera. Twice it was the case that 3 landing attempts were needed.

Visual Discussion

Let's consider the landing image 1.17. The final landing sites indicated in green span exclusively decent landing areas. The verification attempts that fell short are indicated with yellow and annotated by a line connection to the successful attempt thereafter. Subsequent landing sites were always detected short distances away from failed candidates which is exactly the correct behavior in order to not lose time pursuing a far away follow-up landing site. As indicated in ?? this is thanks to the verification altitude which incentivizes the selection of other landing sites detected at the current verification altitude. Lastly the attempt which chose a landing sites before losing the connection to the flight controller is indicated in red. The last thing to mention is the clustering of the landing sites around the takeoff location. The reason for this is twofold:

- Quality:

The takeoff position in the simulation was chosen to be at the same location where the field tests were started in the real world. It was chosen exactly because of its even and smooth characteristics. Therefore, it is no surprise that many landing sites were detected around that location.

- OMG Conversion:

During ascent, when using either stereo or ground truth depth, the same area is perceived repeatedly. This leads to a convergence of OMG certainty in the map aggregation step of LSD. As landing sites have a higher chance of being detected on terrain with a low uncertainty, this converged takeoff area is most likely selected repeatedly and sent to the autonomy until it leaves the rolling buffer map.

Note: the autonomy accounts for repeated detection of the same landing site. LSD however does not. Therefore, in such a case where the same terrain has been viewed for a long period, it is possible for the exact same landing site proposals to be sent to the autonomy repeatedly.

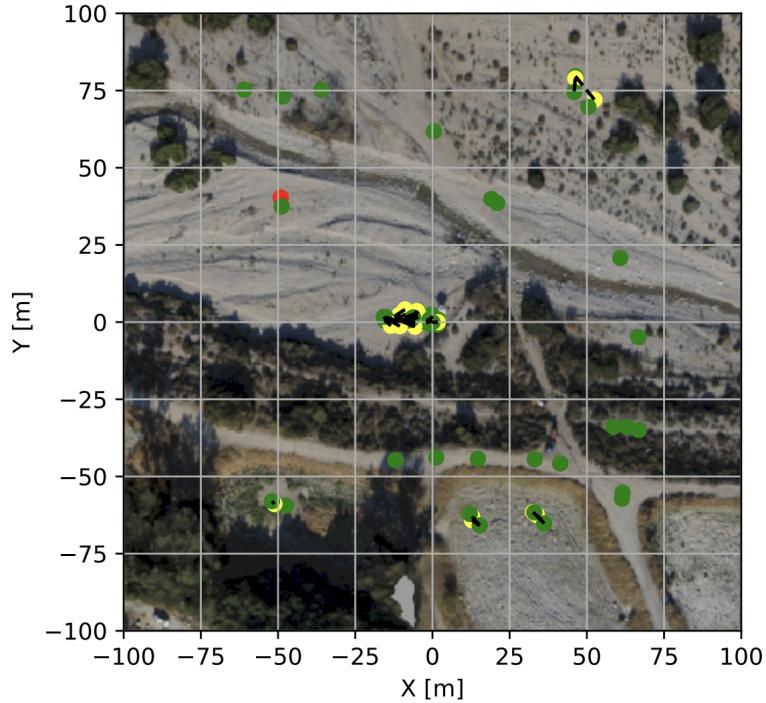


Figure 1.17: Landing Attempts - Green: successful landing, Yellow: verification failure, Blue: landing at home position

This test is a very clear demonstration of the applied chosen heuristics. The best landing site detected is very likely one that is detected at the takeoff position. Around this clustering of landings there is notable space of no attempts performed. This can be attributed to the competing motives of the landing site selection. The quality of the landing site defines the autonomy's choice until the drone's distance to that landing site is too big, and a closer one is chosen.

1.4.2 Arroyo - Randomized Takeoff and Waypoints

In this set of test flights, randomized takeoff positions were used as shown in fig. 1.14. Missions were built using a randomized waypoint in a 70x70m surrounding.

The numerical results look as follows:

Table 1.4: Results with random takeoff location and random waypoint

# Flights	# Successes	# Con. Losses	# Crashes	# Home Landing
100	94	6	0	0

Table 1.5: Landing attempts with random takeoff and random waypoint

# LS Landings	# 1 attempt	# 2 attempts	# 3 attempts	# 4 attempts
94	88	6	0	0

And the visual outcome is shown in fig. 1.18.

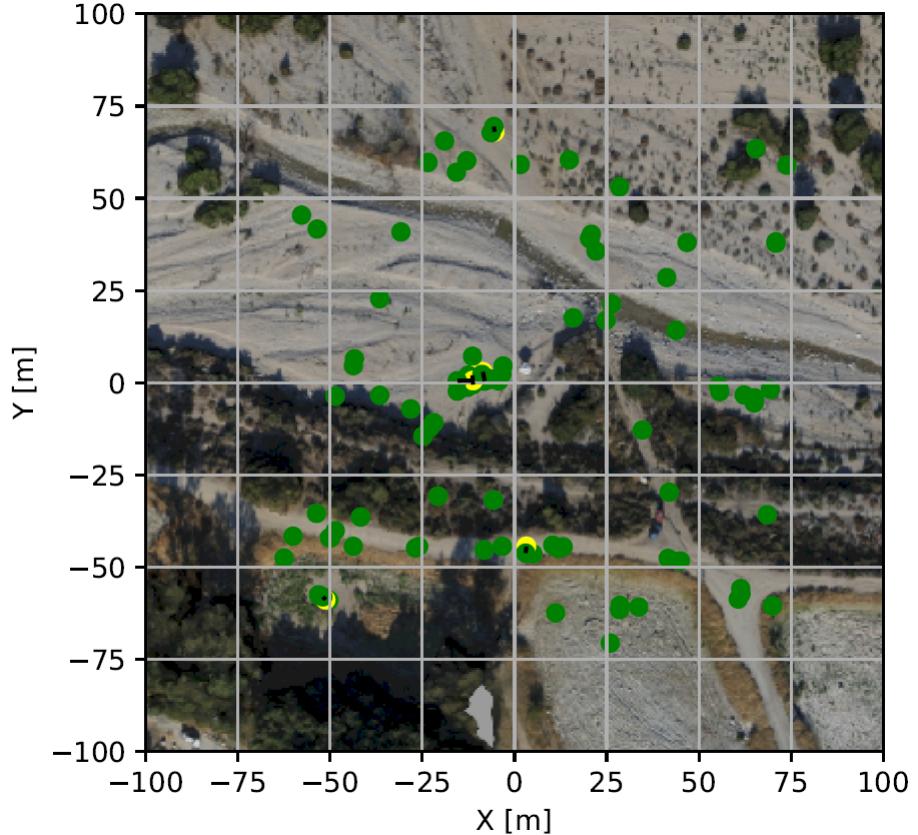


Figure 1.18: Landing attempts with randomized drone spawn - Green: successful landing, Yellow: verification failure, Blue: landing at home position

Numeric Discussion

6 timeouts occurred in this 100 flight experiment. Of the successful 94 runs, 88 landed at the very first attempt and only 6 needed one more landing site. This is a pleasant outcome which is of course correlated with the ground truth's high accuracy. Nevertheless, it has to be noted that multiple landing attempts at different sites is no indication of inferior performance.

The relatively high number of timeouts is unfortunate but as previously mentioned, not a fault of the presented pipeline and therefore merely unfortunate but not worrying.

Visual Discussion

Compared to fig. 1.17, the landing attempts are more spread out over the map and fewer landings were attempted at the takeoff position. This is the case because the random mission trajectories didn't always cover this area and since the drone spawned at randomized locations, it did not spend the time during takeoff to repeatedly scan this plateau. Thus, the elevation map did not converge at that location leading to a smaller chance of landing sites being detected there.

As for the fixed spawn location, the second attempts were always at landing sites which were close to the false previous candidates. This is of course desirable to save time.

Lastly, the selected landing sites were all at plausible locations. To verify this, consider the empty reference image shown in fig. 1.16

1.4.3 Rough Map - Mission Covering Platforms

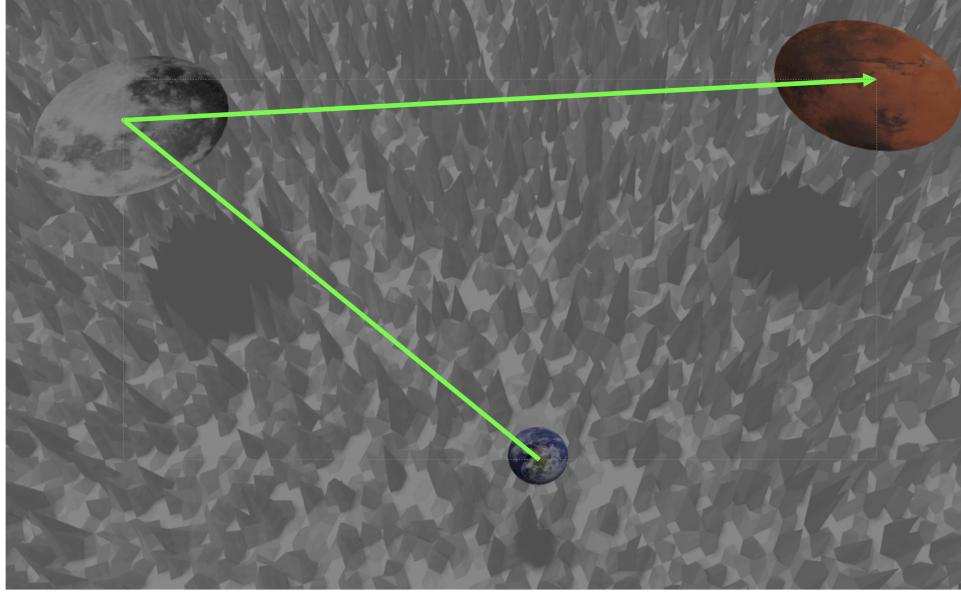


Figure 1.19: Test flights on rough map with waypoints covering the landing sites

In this test, the drone flew a randomized two-waypoint pattern which always covered the synthetically added landing platforms. The idea behind this experiment was to eliminate other landing possibilities and test, whether the approach at hand would be able to detect the controlled good landing sites.

The numerical result thereof is displayed below:

Table 1.6: Results - Rough map with platform coverage

# Flights	# Successes	# Con. Losses	# Crashes	# Home Landing
100	99	1	0	0

Table 1.7: Landing attempts rough map with platform covering mission

# LS landing	# Landing on first attempt	# 2 attempts	# 3 attempts
99	98	1	0

As both the spawn platform and the landing platforms where spawned randomly, evaluating the visual outcome is redundant. For sake of completion however, it is still displayed in fig. 1.20.

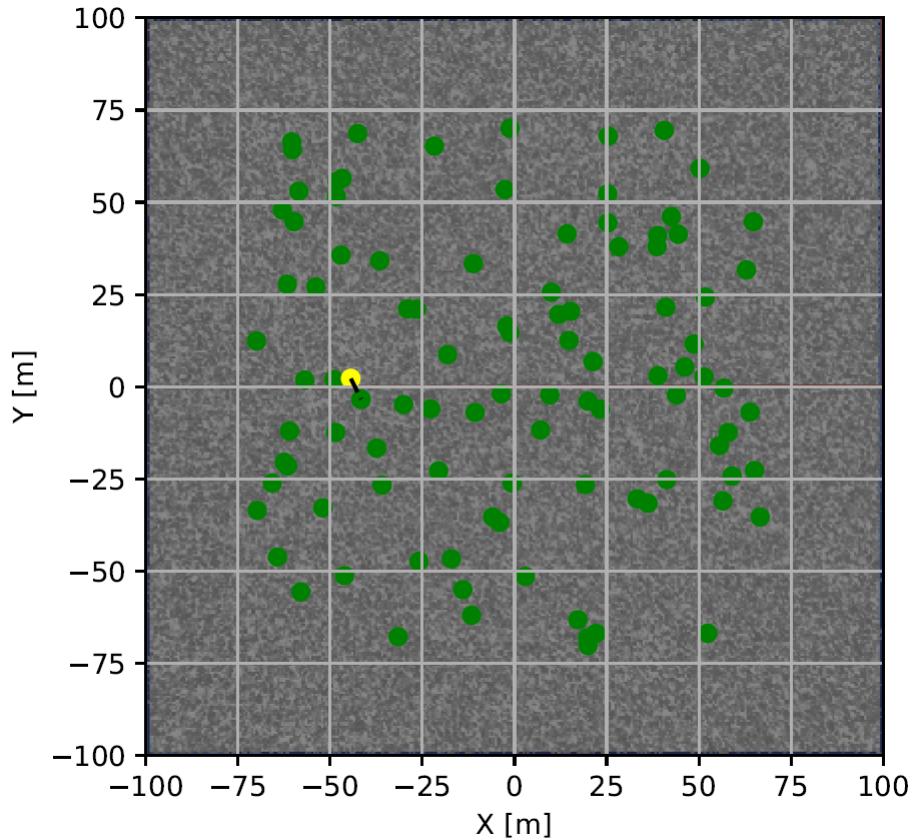


Figure 1.20: Landing attempt locations for the rough map with platform covered by the mission

Numerical Discussion

One timeout occurred and one verification failed. The residual flights all succeeded on the first landing site detected.

All landing site candidates except one were verified. This convincing result is not surprising as the inserted landing sites are very high quality landing sites and are therefore unlikely to trigger a verification failure. The verification rate is not perfect however, as the landing sites were only thin disks as shown in fig. 1.12.

To determine the pipeline's ability to choose the best available landing area, the final landing locations were compared to the platforms spawned. This was the result:

Table 1.8: Final Landing Platform Choice

# Landings	# On Earth (spawn)	# Moon (1st pf)	# Mars (2nd pf)
99	4	2	93

Table 1.9: Landing locations chosen by this experiment - The Earth platform denotes the small spawn location of the drone. The Moon corresponds to the platform covered by the first mission waypoint and the Mars platform is where the missions ended.

This result shows as desired, that the last platform which is the one closest to the drone at the time of the last waypoint, was chosen most of the time.

When the Earth platform, which is the takeoff location, was close enough to the last waypoint, it was sometimes chosen because the landing sites discovered on it during takeoff were detected closer above ground than the ones at course altitude. The same happened when the first platform could be seen during ascent and was relatively close to the last waypoint.

1.4.4 Rough Map - Random Waypoints

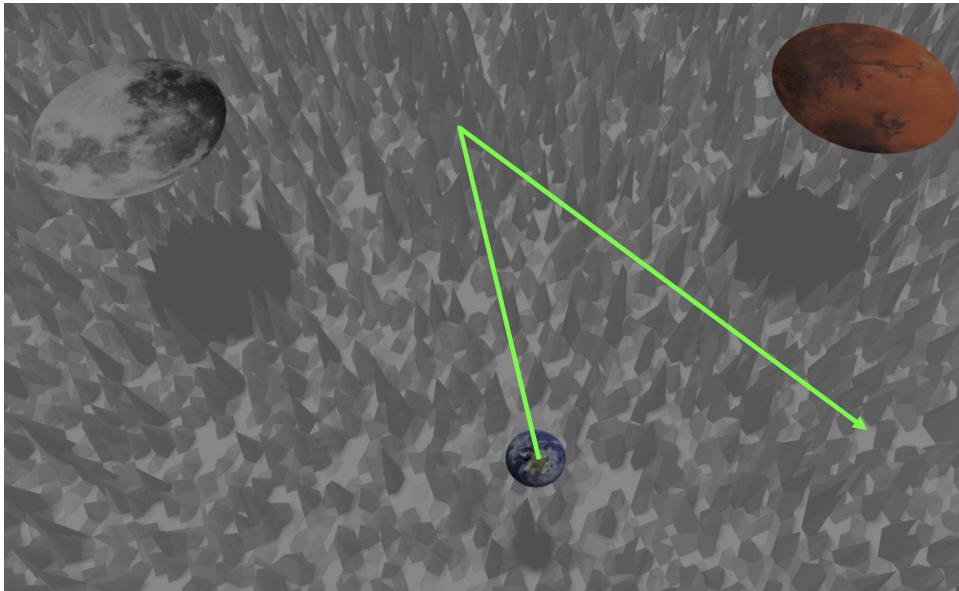


Figure 1.21: Test flights on rough map with waypoints covering the landing sites

Changing the setup a bit, in this test, the drone flew a completely randomized two-waypoint pattern without the guarantee of flying over a safe landing site. This test set analyzed the pipeline's capabilities to deal with the case when no landing sites are detected initially.

First, in this experiment of 100 flights when the drone did not detect any landing sites, it flew only minimal landing site search patterns of 1 m radius. This should serve as a baseline to see how many sites are approximately found without significant additional search actions.

The numerical result thereof is displayed below:

Table 1.10: Results - Rough map with platform coverage

# Flights	# Successes	# Con. Losses	# Crashes	# Home Landing
100	98	2	0	54

Numerical Discussion

Looking at table 1.10, what stands out are the 54 times the drone went to the home position. This is the desired behavior, when no landing site is found and is therefore to be considered a success. It is also rather expected as the minimal search pattern

Table 1.11: Landing attempts rough map without platform covering mission

# LS landings	# Landing on first attempt	# 2 attempts	# 3 attempts
44	43	1	0

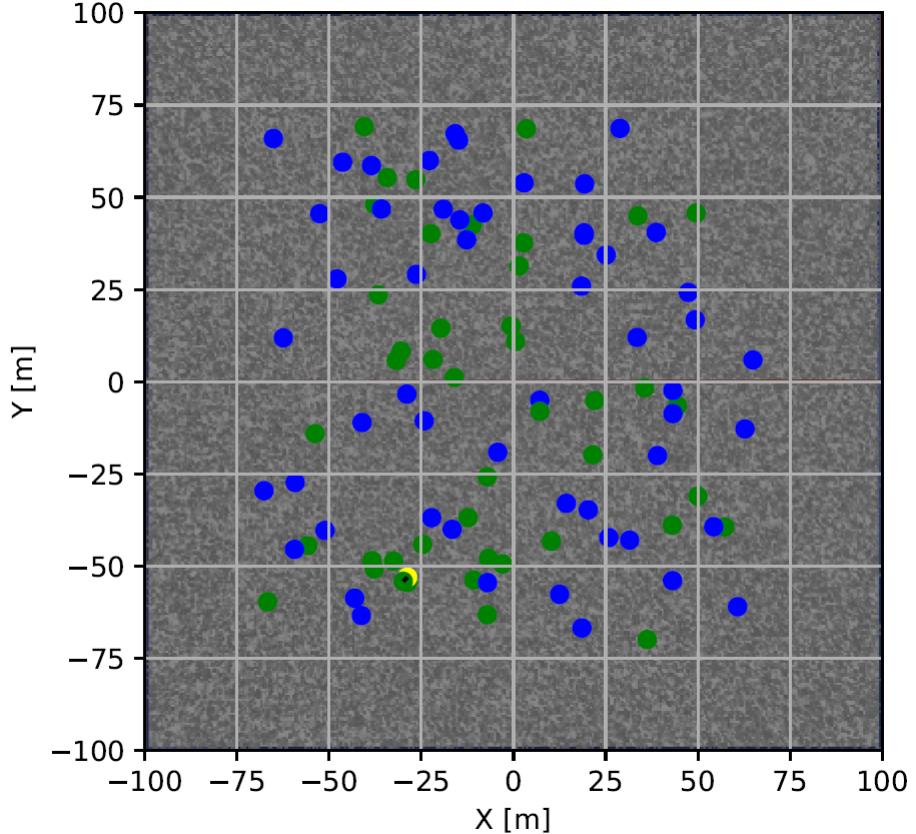


Figure 1.22: Landing attempt locations for the rough map with completely random missions

radius likely prevents the drone from finding additional landing sites. Like for the case when the platforms were covered by the mission waypoints, the landing sites were almost always verified as they were by design of high quality.

1.4.5 Rough Map - Random WPs with Larger Search Radius

When flying the same experiment setup as introduced in section 1.4.4 but with a larger search pattern radius we arrive at the following outcome:

Numerical Discussion

Compared to the same randomized run on the hostile terrain shown in section 1.4.4 the drone went home only 34 times as opposed to the previous 54. This shows the impact of the additional search patterns flown when no platforms are seen during the mission.

6 times a second landing site had to be chosen. These were all picked on the same platform the initial landing was attempted.

Table 1.12: Results - Rough map with platform coverage

# Flights	# Successes	# Con. Losses	# Crashes	# Home Landing
100	98	2	0	34

Table 1.13: Landing attempts rough map without platform covering mission

# LS Landings	# Landing on first attempt	# 2 attempts	# 3 attempts
66	60	6	0

1.4.6 Arroyo - Randomized Takeoff and Mission with SFM

As mentioned in section 1.1, SFM’s implementation at the time of this work was not well suited for high altitude flights. For sake of completeness however, the pipeline was flown with SFM and analyzed in the following.

The setup was the same as for section 1.4.2 with randomized spawn and mission locations. However, this time SFM was used for the depth generation.

Table 1.14: Results - SFM with random spawn and way points

# Flights	# Successes	# Con. Losses	# Timeouts	# Home Landing
100	77	18	0	5

Numerical Discussion

Compared to the other tests, in this setting many connection losses occurred. Additionally, the nominal procedure timed out 5 times meaning that numerous landing site verifications were necessary which in the end prevented the flight from completing within the 10 minutes before the next iteration was started.

This occurred because of two reasons:

- The landing site proposals supplied by SFM are of less quality than the ground truth leading to a higher probability of necessitating the selection of another landing site.
- Secondly, overruling SFM measurements using stereo inputs takes substantial time. In practice the 15 s verification duration was not always sufficient to yield good estimates of the surrounding. Because of this, further landing sites of lower quality were selected which were detected on SFM data from 100 m altitude. This lead to further failures. Secondly, these landing sites were also more often farther away which made the procedure slower still.

This definitely has to be accounted for. As mentioned in ??, a potential remedy for excessive convergence could be time inflation of the OMG cell’s of the elevation map.

Visual Discussion

The first thing to note is the high number of red points. This is both because of the numerous connection losses and because of the landing attempts which took too

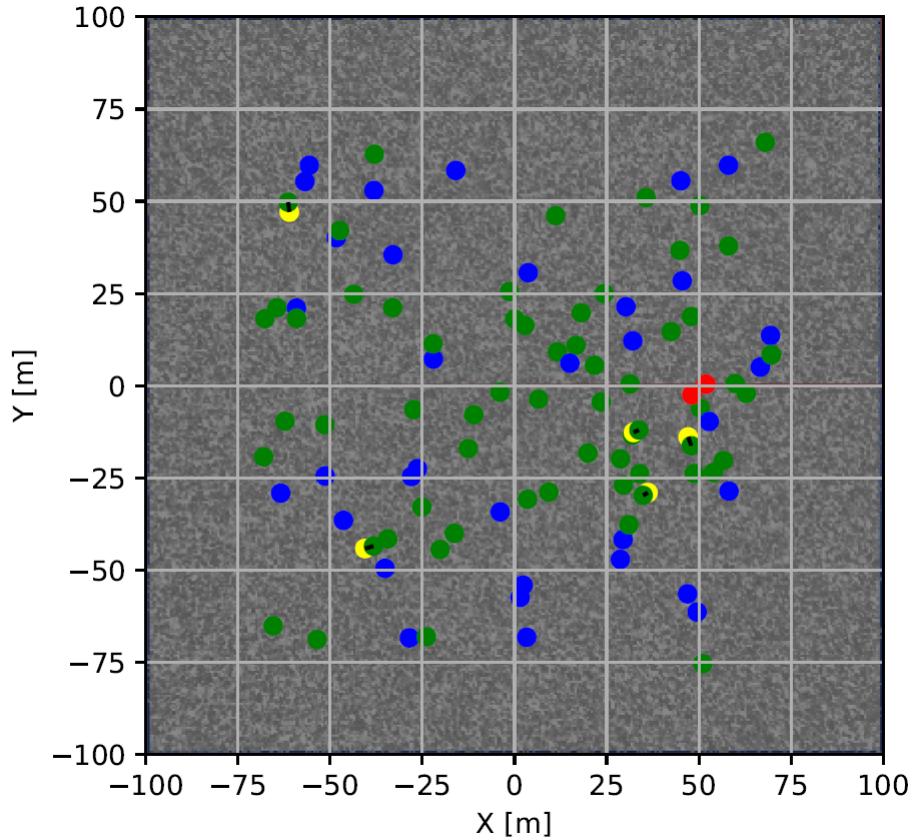


Figure 1.23: Landing attempt locations for the rough map with completely random missions and an increased landing site search action radius

Table 1.15: Landing attempts of successful flights when flown with SFM

# Flights	# 1st attempt	# 2 attempts	# 3 attempts
77	45	30	2

long and therefore didn't lead to a landing. The landing sites are in general of less quality than for the GT cases. Lastly as can be seen in a successful run, subsequent landing sites were not always close by. As previously mentioned this occurred when the stereo measurements did not overwrite the SFM information in time so that other, far away SFM landing sites were selected.

1.5 Theoretical Edge Cases

section 1.4 shows that the implemented landing procedure performs well only terrain that is roughly comparable to that on Mars. These tests represent rather ordinary cases though. In the following, a number of theoretical edge cases are introduced and their handling by this work's pipeline discussed.

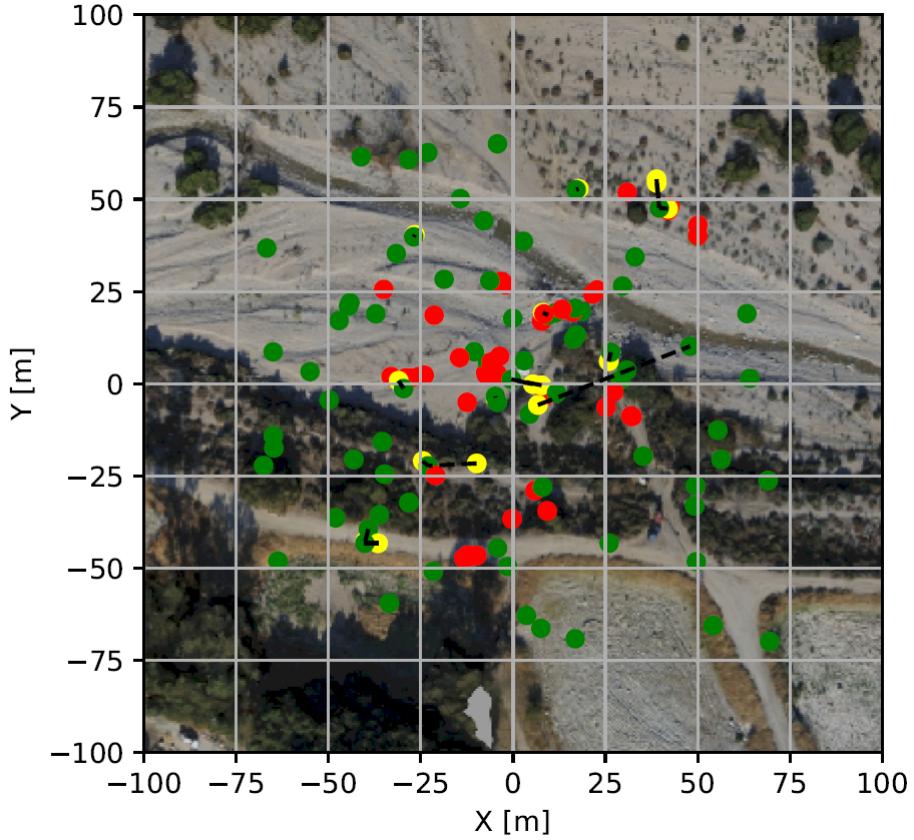


Figure 1.24: Landing attempt locations when flying a mission with randomized drone spawns and randomized way points with SFM

1.5.1 Arrival on Mars

One concept for the rotorcraft arrival on Mars is its takeoff during the descent of the main payload. In the Mars Sample Return mission which has since been aborted for instance, this payload would have been the landing platform to return the Mars samples to. From that lander the rotorcraft would take off mid-descent and land on its own.

Playing this scenario through, a small mission or pattern needs to be flown in order to move laterally and thus detect landing sites. Additionally, as the platform from which we took off is descending with neck-breaking velocity, we need to consider a different location for the choice of our home position. This can be done prior to the flight using a mixture of HiRISE orbiter images and information provided by Opportunity and Ingenuity. The ladder two options also ensure a sufficient image resolution to safely determine a home position.

In case of successful landing site detection during this mission, the landing procedure is initiated as usual. If no candidates for suitable landing areas were found however, further landing site search patterns at random locations are flown. If the landing site buffer remains empty still, the aforementioned synthetic home position is navigated to and landed at.

1.5.2 Flying on Large Scale Inclined Terrain

The tests performed all happened on generally even terrain with rough and inclined areas spread throughout. What happens however, when we want to fly the drone over large scale inclined terrain? An example of this could be flying out of the Jezero crater which is where the Opportunity rover was deployed.

In this case, the necessary precautions must be taken during the mission planning stage. Assuming a mission was created at a cruise altitude high enough to allow lateral traversal to the farthest mission waypoint without danger of collision, the landing behavior would be the same.

Two possible break points exist however:

- Lack of number and quality of landing sites

On inclined terrain fewer landing sites are detected. Secondly, a blind spot of the pipeline are unstable landing sites like larger rocks. Though the probability of landing on such a rock and thus making it fall over are very small, they exist. Even more so on inclined terrain.

- Collision danger when flying LS search patterns

The mission waypoints are set deterministically. Therefore, the terrain can be accounted for during their creation.

This is not the case for the random flight patterns execute when no landing sites are available. The center point of a rectangular search pattern is set randomly at a fixed distance from the location where the action was invoked. If during the mission a landing site was found at a very high altitude and turned out to be a false candidate, the LS search is initiated at that location. This case is schematically depicted in fig. 1.25. Note how the found landing site was detected at a significant distance from the last mission waypoint.

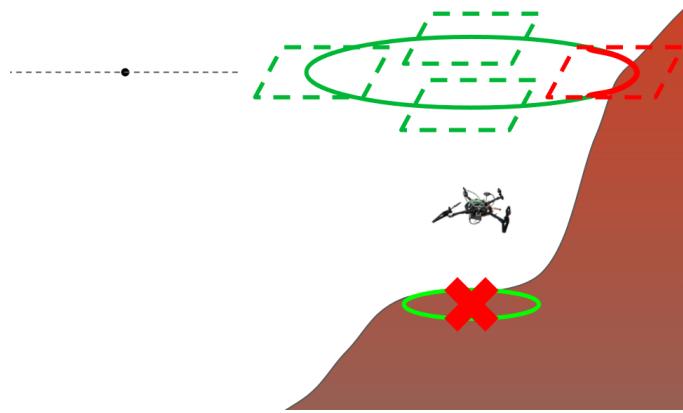


Figure 1.25: Break case of landing site search pattern. The black dot indicates the last mission waypoint at cruise altitude. The bright green circle with the red cross show an invalid landing site and the circle above the drone shows the possible center points of search patterns.

One more break case for the presented pipeline is overhanging terrain. In that case the ascent to a clearing altitude does not constitute a safe approach.

It has to be noted however, that the exploration of terrain as advanced as overhanging ground and cave systems is not considered part of the LORNA endeavor.

Bibliography

