

Marine plastic pollution is a large issue these days. Removal of marine plastic pollution is sadly an underrepresented topic in research and development. This report continues work on a simulation and control system intended for a solution that will remove marine plastics. The system consists of an unmanned surface vessel and a negatively-buoyant remotely operated vehicle with a gripper attached. Because the remotely operated vehicle is negatively buoyant, the two vessels are coupled, meaning that the movements of one inherently affects the movements of the other. This provides interesting control challenges.

In this project, a simulator and control system have continued development from a previously made baseline, and the system has been simulated in various sea states. The results show that the controller is currently not tuned well enough and that the simulation has some work to be done, but the results are nonetheless promising.

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Plast i havet er et stort problem i disse dager.