Model-Based Development of an Underwater Vehicle

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Model-Based Development of an Underwater Vehicle

2016-06-01

- Model-based design development
- Control system

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Bluerov I/O sensorfusion

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└─Modelling the ROV

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what is a model and be used for damping - linear quadratic Coriolis
restoring forces added mass and added moment of inertia
simplifications and why they are needed

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└─Parameter Estimation

What is parameter estimation and why is it needed pem and problems kalman smoother pem results kalman estimation kalman results discussion

2016-06-01

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problems kalman smoother pem results kalman estimation kalman
results discussion

what is automatic control open-loop control exact linearisation
attitude angular velocity depth results discussion

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└─Conclusion

what is automatic control open-loop control exact linearisation
attitude angular velocity depth results discussion