Autonomous quadcopter for rapid underground mine mapping and exploration

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Abstract. Mine surveying and mapping is a time-consuming and hazardous task that is critical to most underground mining operations. Recently, the introduction of robotics for underground mine mapping has reduced these safety risks for humans. This project aims to develop an autonomous quadcopter equipped with dedicated sensors capable of performing 3D SLAM (Simultaneous Localization and Mapping) in GNSS (Global Navigation Satellite System)-denied environments, such as underground mine sites. Various localization and mapping algorithms were compared and tested, and the SpectacularAI package proved to be a computationally efficient SLAM method that can run on the quadcopter’s onboard computer, creating dense and detailed point cloud maps. Additionally, autonomous exploration and path planning methods for three dimensional spaces were analysed and appropriate algorithms were employed to complete the platforms autonomy necessary due to the communication lacking subterranean environment.

1. Introduction

Given the significant human safety and health hazards in underground mines—including fires, rock falls, gas leaks, and floods [3]—robots have recently been deployed to assist with underground mine surveying, environmental monitoring, and exploration. Such robotic platforms include autonomous rovers for underground 3D mapping using rotating lidar sensors [4] and composite systems like the Rhino, which utilize lidar and RGB-D fusion for underground localization and mapping [5]. More recent approaches extend these capabilities through multi-robot exploration, mapping, and terrain perception by networking platforms such as quadrupeds, rovers, and UAVs (Unmanned Aerial Vehicles) [6]. UAVs, in particular, serve as rapid exploration tools that provide fast data collection and extensive coverage, with most of these platforms relying on lidars to perform SLAM algorithms [7]. Additionally, UAVs can navigate challenging terrain conditions—such as extreme slopes, water pools, tight spaces, and vertical shafts—where quadrupeds and rovers often struggle [7]. Additionally, subterranean environments present a significant need for autonomy due to limited communication capabilities and their intricate layouts necessitating low latency, real time decision making [6]. The aim of this project is to design and develop a small-scale, agile quadcopter that performs onboard SLAM and autonomous exploration in underground mines, delivering a comprehensive 3D representation of the environment.

1. Methodology and Results

The developed platform, called Void Raven, consists of a custom-built 5-inch quadcopter with components specifically chosen for performance and efficiency to maximize the UAV’s permittable payload and exploration time. Additionally, the quadcopter is equipped with a Pixhawk 6C Mini Flight Controller running PX4, which handles low-level flight control and facilitates processes such as position estimate calculations.

Additional components integrated into the platform include a Khadas Vim4 running Ubuntu 22.04 and ROS2 for onboard computing, a Here Flow optical flow sensor to aid with position control in the absence of GNSS in underground environments, and an OAK-D Pro W RGB-D (Red, Green, Blue-Depth) camera that provides depth information and generates a point cloud for on board SLAM and autonomous exploration. An RGB-D camera was chosen over the commonly used lidar because it is significantly lower in cost, provides more visual information—including surface texture and colour—and has lower power consumption. A detailed image of the platform is shown in Figure 1.

A room with a building and a window

AI-generated content may be incorrect.Careful considerations were required when selecting SLAM algorithms due to the Vim4's limited computational power and its arm64 architecture, while most SLAM solutions are developed for powerful AMD64 platforms. After thorough evaluation and testing, it was decided to employ the SpectacularAI package to perform SLAM. This package was modified such that its native HybVIO module, which fuses visual odometry with IMU (Inertial Measurement Unit) data to track the camera's position [8] is incorporated into the Flight Controllers EKF (extended Kalman filter) to obtain a more robust Global position estimate. Furthermore, the packages inherent OpenVSLAM package—a re-implementation of ORB-SLAM2—is employed for loop closure optimization [9]. Figure 2 shows a point cloud map created by the system, after down sampling and removal of outliers has been performed onboard. For this test, the UAV was teleoperated up a flight of stairs, through a foyer, and into a passageway.

Fig. 2. Point Cloud Map created using the developed platform

Fig. 1. Detailed Picture of the Platform

The resultant local map point clouds were further used to create a probabilistic volumetric occupancy grid using OctoMap[10] which is of special interest to the autonomous navigation suite, due to its reduced complexity. Finally, various methods of autonomous exploration algorithms including global planner and local planners were deployed and tested on the platform. The RRT algorithm prove to be computational efficient enough to run on the Khadas Vim4, while providing quick exploration capabilities. This however comes at a cost of sometimes choosing slightly suboptimal paths.

Conclusion

A quadcopter capable of autonomously exploring and mapping GNSS-denied environments, such as underground mines, was successfully developed using cost-effective and energy-efficient components. The deployed software suite was tested and proved to generate a point cloud map of its environment containing detailed features. Additionally, the RRT path planning algorithm was used to enable the platform to rapidly explore environments, even though it sometimes tended to choose slightly sup-optimal paths. Finally, the platform could further be improved by integrating precision landing and data deployment to integrate it with other platforms, enabling multi agent exploration.

References

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