



UNIVERSITAT POLITÈCNICA DE CATALUNYA
BARCELONATECH

Escola Superior d'Enginyeries Industrial,
Aeroespacial i Audiovisual de Terrassa

Real-Time Optimal Trajectory Generation for Fixed-Wing UAVs in Firefighting Missions via Numerical Integration and Constrained Optimization

Document:

Report

Author:

Abimael Campillo Simón

Director/Co-director:

Prof. Dr. Alex Ferrer Ferre / Miguel Pareja Muñoz

Degree:

Bachelor in Aerospace Technology Engineering

Examination session:

Autumn 2025

BACHELOR FINAL THESIS

Abstract

Acknoledgments

,3Lorem ipsum dolor sit amet, consectetur adipiscing elit. Ut purus elit, vestibulum ut, placerat ac, adipiscing vitae, felis. Curabitur dictum gravida mauris. Nam arcu libero, nonummy eget, consectetur id, vulputate a, magna. Donec vehicula augue eu neque. Pellentesque habitant morbi tristique senectus et netus et malesuada fames ac turpis egestas. Mauris ut leo. Cras viverra metus rhoncus sem. Nulla et lectus vestibulum urna fringilla ultrices. Phasellus eu tellus sit amet tortor gravida placerat. Integer sapien est, iaculis in, pretium quis, viverra ac, nunc. Praesent eget sem vel leo ultrices bibendum. Aenean faucibus. Morbi dolor nulla, malesuada eu, pulvinar at, mollis ac, nulla. Curabitur auctor semper nulla. Donec varius orci eget risus. Duis nibh mi, congue eu, accumsan eleifend, sagittis quis, diam. Duis eget orci sit amet orci dignissim rutrum.

Preface

,10Lorem ipsum dolor sit amet, consectetur adipiscing elit. Ut purus elit, vestibulum ut, placerat ac, adipiscing vitae, felis. Curabitur dictum gravida mauris. Nam arcu libero, nonummy eget, consectetur id, vulputate a, magna. Donec vehicula augue eu neque. Pellentesque habitant morbi tristique senectus et netus et malesuada fames ac turpis egestas. Mauris ut leo. Cras viverra metus rhoncus sem. Nulla et lectus vestibulum urna fringilla ultrices. Phasellus eu tellus sit amet tortor gravida placerat. Integer sapien est, iaculis in, pretium quis, viverra ac, nunc. Praesent eget sem vel leo ultrices bibendum. Aenean faucibus. Morbi dolor nulla, malesuada eu, pulvinar at, mollis ac, nulla. Curabitur auctor semper nulla. Donec varius orci eget risus. Duis nibh mi, congue eu, accumsan eleifend, sagittis quis, diam. Duis eget orci sit amet orci dignissim rutrum.

Scope and Objectives

Motivation and Justification

Methodological Approach

Document Structure

.

Contents

1	Fundamentals of Optimal Control and its Implementation	1
1.1	Introduction to Optimal Control Theory	1

List of Figures

List of Tables

Acronyms

NLP Non-linear Programming.

OC Optimal Control Problem.

OCT Optimal Control Theory.

1 | Fundamentals of Optimal Control and its Implementation

1.1 Introduction to Optimal Control Theory

The Optimal Control Theory (OCT) is a control field related branch where an objective function has to be optimised -most of the times, it has to be minimised- in order to find the control trajectory for a determined dynamical system. This theory is hystorically realted with calculus of variations, where optimal points -either maxima or minima- are found using lñittle variations in functions or functionals (CITA). This field of study, proposed by Isaac Newton, was developed as a solving approach for the brachistochrone problem, posed by Bernoulli in 1696. The brachistochrone curve is defined as the fastest descent path -most optimal path for minimising time- between two points A and B under a uniform gravitational field. Counterintuitively, it was found that the most optimal path was not but the cycloidal ramp, as can be seen on the image below, where ball has to roll under gravity only atbthe different paths, and the same grade shaded figures correspond to same time-instants.

In essence, the OCT responds the need to solve continuous time optimisation problems, as the once presented. Thus, the Optimal Control Problem (OC) can be understood as a n-dimensional extension of the Non-linear Programming (NLP) problem. The NLP problem can be defined as the minimisation of a given function subject to a different set of equations or inequations, called constraints.