



An autonomous time dependent swarm routing system for real time investigation

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Autonomy

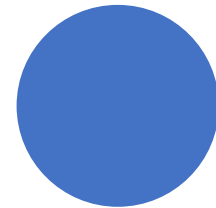
- Fully autonomous systems?
- Cognitive autonomy
- Computer vision
- System on Chips (NVIDIA, Intel)
- Open Source (Dronecode, Tango, CUDA, OpenCV)

Vehicle Routing Problem

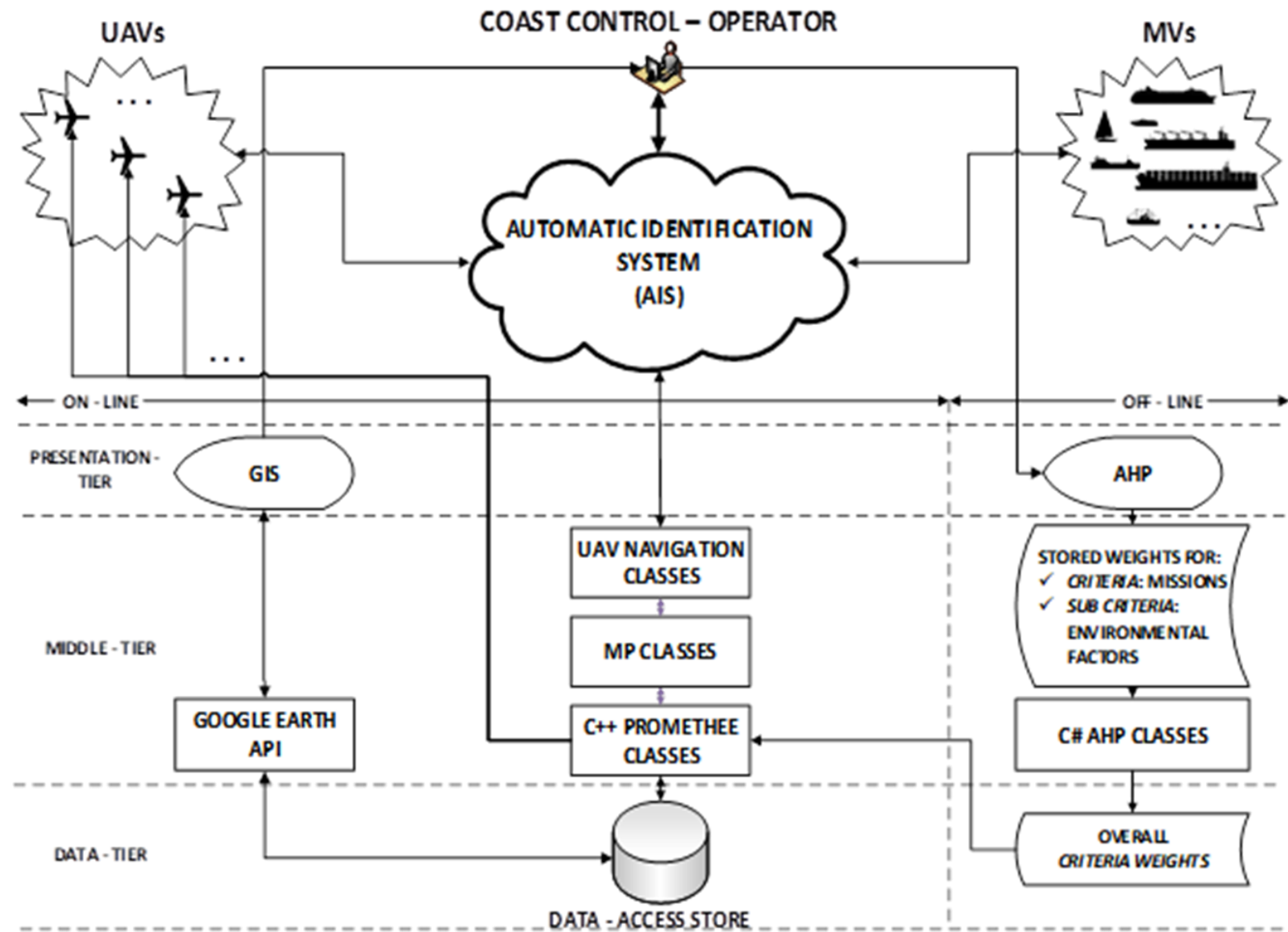
- TSP
- VRP taxonomies (Dynamic Deterministic)
- Moving target TSP
- Genetic algorithms
- Ant colony algorithms
- Objective optimization
- Multi criteria decision analysis (MCDA) methodologies
- MCDA routing
- MCDA integration

- AHP
- PROMETHEE
- MP
- GIS

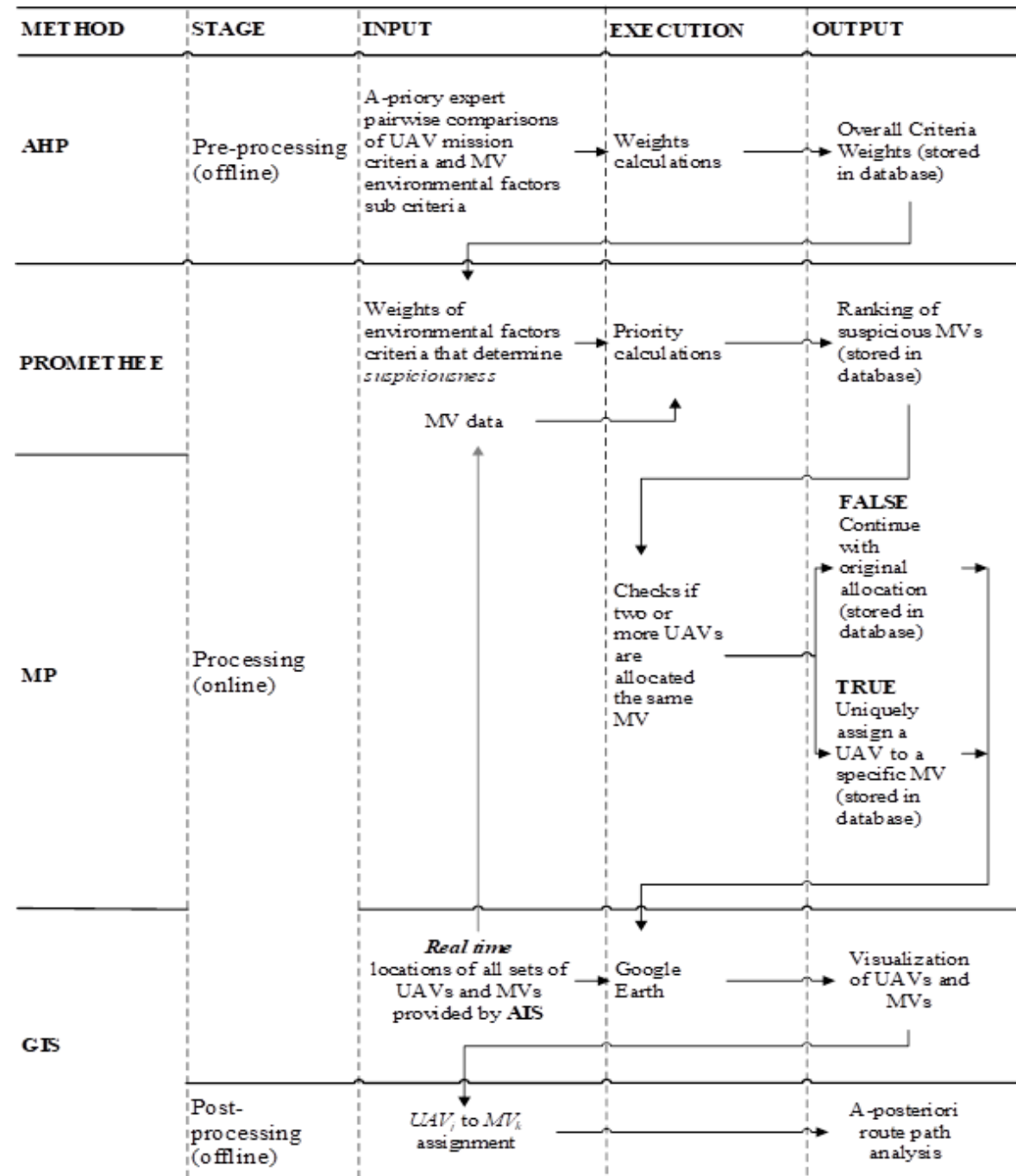
Time dependent MCDA



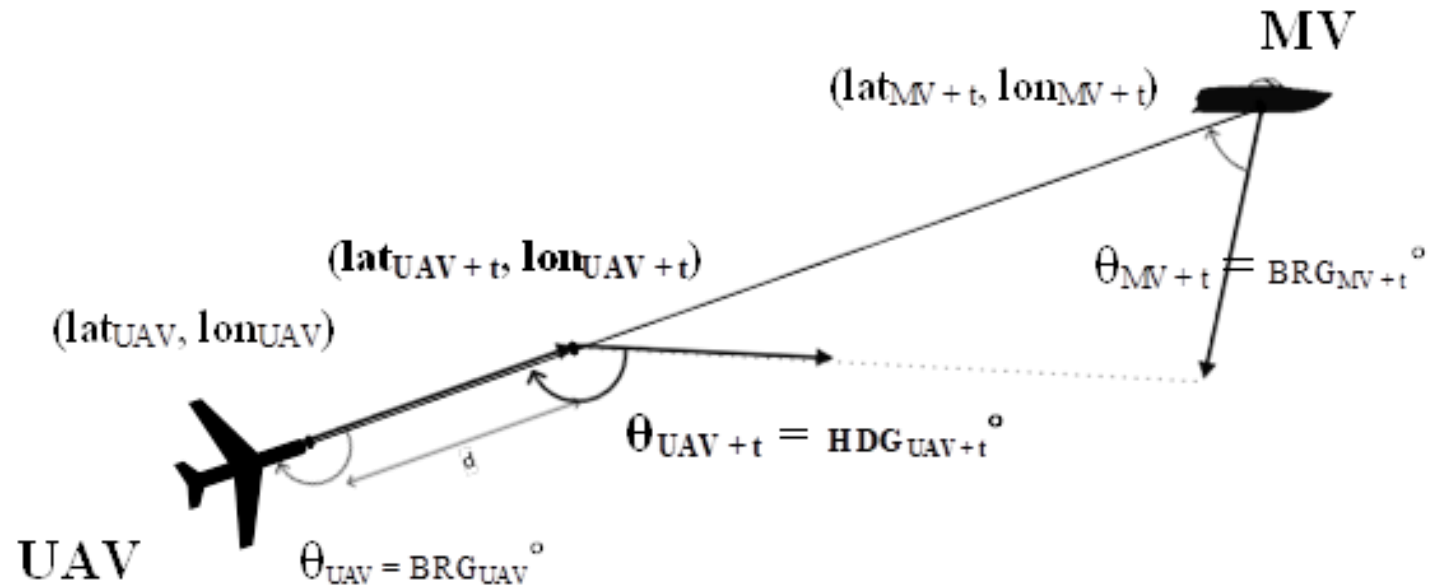
Overview



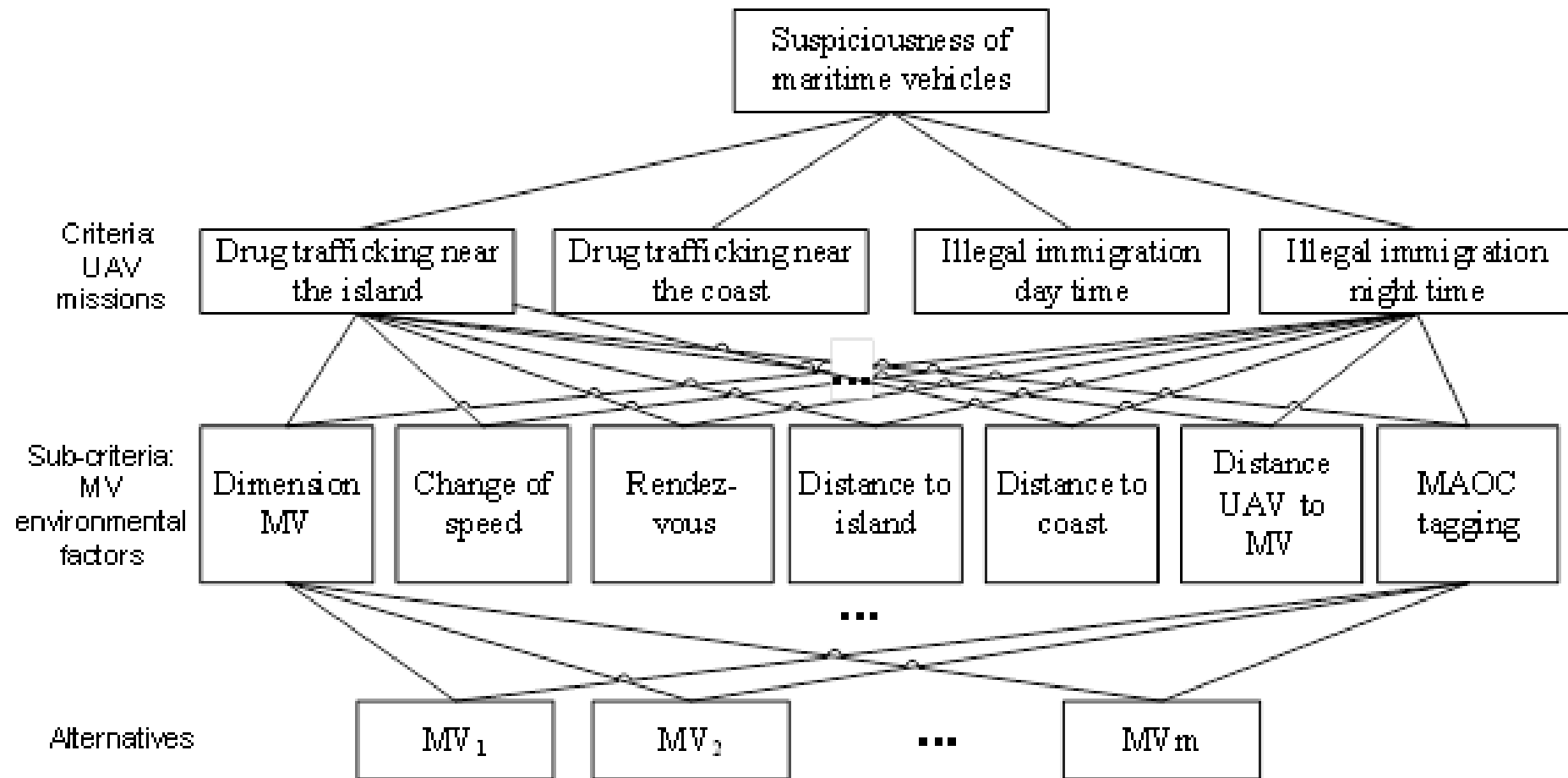
Autonomy algorithm



Autonomous navigation based on suspiciousness



Mission – Envir. factors modelling



Mission priorities

Priorities	UAV_1	UAV_2
Drug trafficking near the island	0.1307	0.1249
Drug trafficking near the coast	0.0488	0.6925
Illegal immigration during the day	0.2259	0.0995
Illegal immigration during the night	0.5946	0.0831
Consistency ratio	0.043	0.0001

Target criteria weights

Criteria	Drug coast	Drug sea	Immigration day	Immigration night
Dimension	0.171	0.103	0.092	0.165
Change of Speed	0.039	0.023	0.031	0.144
Rendezvous	0.040	0.321	0.025	0.020
Distance to island	0.034	0.020	0.155	0.063
Distance to coast	0.319	0.033	0.150	0.221
Distance UAV to MV	0.034	0.166	0.030	0.083
MAOC tagging	0.426	0.334	0.518	0.304
Consistency Ratio (CR)	0.06	0.09	0.07	0.09

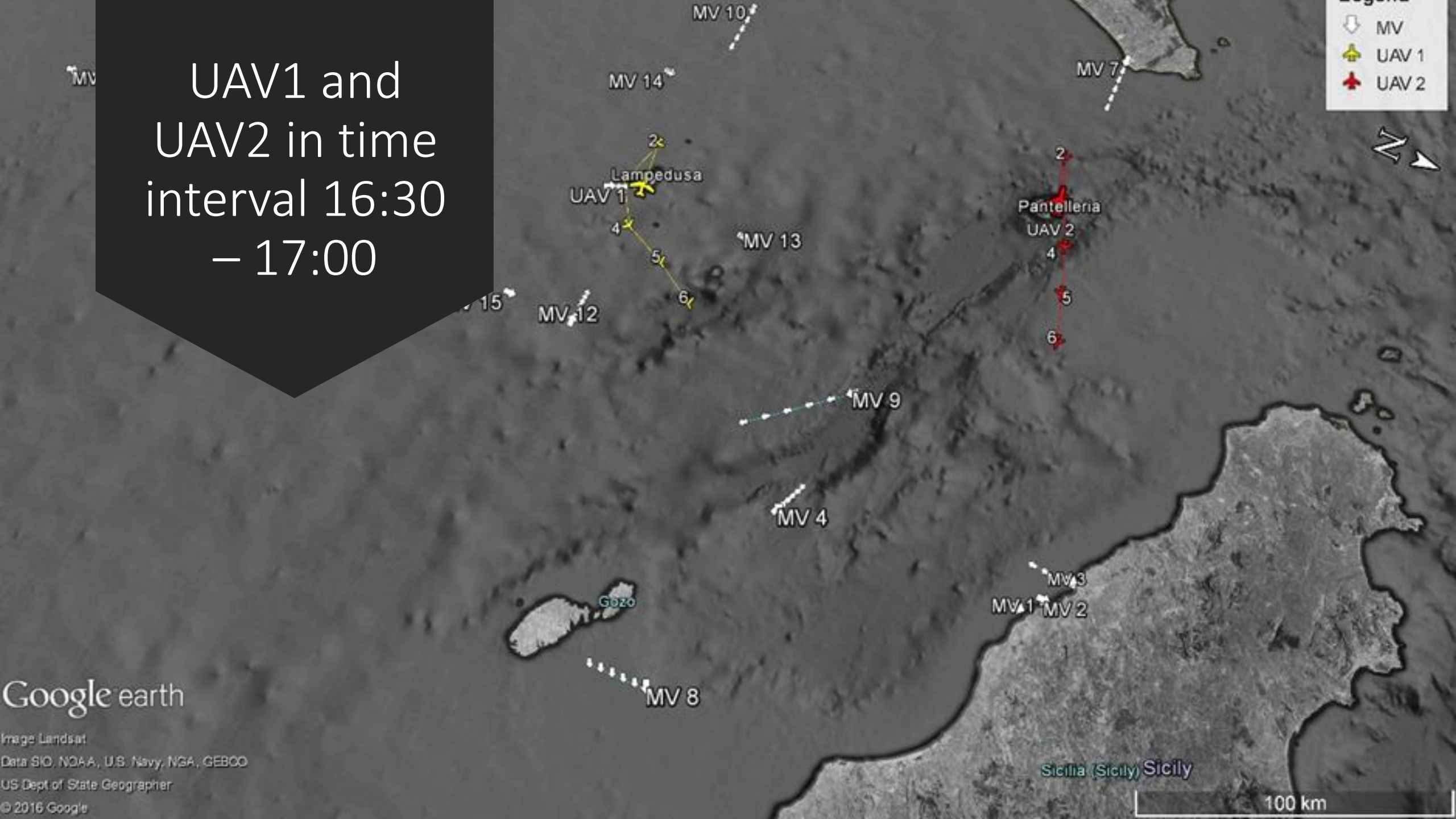
Overall suspiciousness criteria

	Criteria	UAV_1	UAV_2
C ₁	Dimension	0.139	0.111
C ₂	Change of Speed	0.104	0.047
C ₃	Rendezvous	0.062	0.079
C ₄	Distance to island	0.069	0.044
C ₅	Distance to coast	0.184	0.252
C ₆	Distance UAV to MV	0.084	0.059
C ₇	MAOC tagging	0.358	0.408

Legend

- MV
- UAV 1
- UAV 2

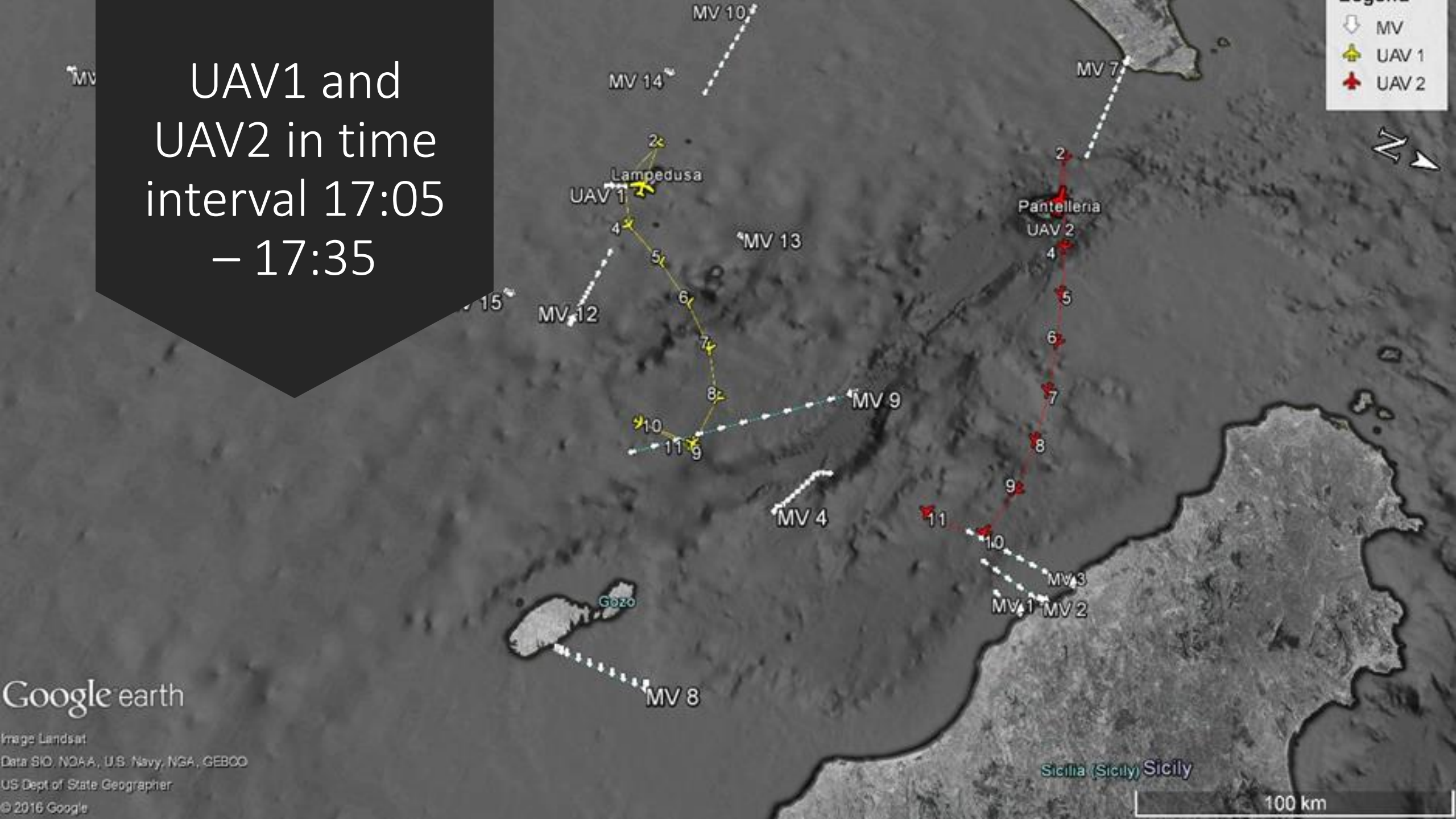
UAV1 and
UAV2 in time
interval 16:30
– 17:00



Google earth

Image Landsat
Data SIO, NOAA, U.S. Navy, NGA, GEBCO
US Dept of State Geographer
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UAV1 and
UAV2 in time
interval 17:05
– 17:35



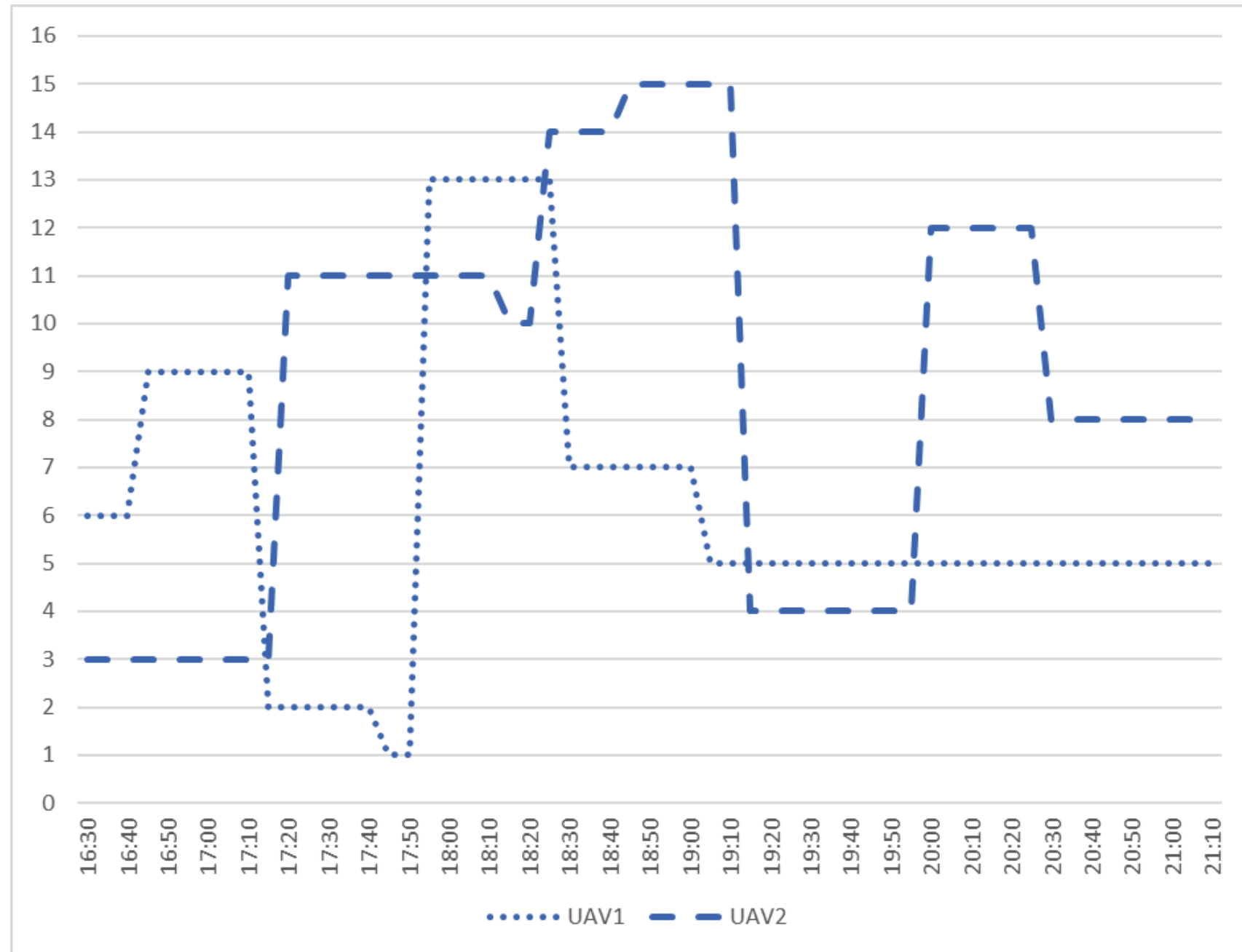


	C ₁	C ₂	C ₃	C ₄	C ₅	C ₆	C ₇	
Min/Max	MIN	MAX	MIN	MAX	MAX	MIN	MAX	
Pref. fn	Linear	Linear	Linear	Linear	Linear	Linear	Linear	
Preference	20	0.001	20	1	1	40	1	
Indifference	8	0	2	0	0	10	0	
Inflection	n/a	n/a	n/a	n/a	n/a	n/a	n/a	
Weight	0.139	0.104	0.062	0.069	0.184	0.084	0.358	<i>MV</i>
								<i>Ranking</i>
MV₁	12	0	9.043	0.691	0.685	207.041	1	0.008
MV₂	8	0	9.043	0.973	0.551	210.297	1	0.023
MV₃	20	0	11.64	0.985	0.908	212.091	1	0.122
MV₄	60	0	46.416	0.919	0.843	135.964	1	-0.236
MV₅	12	0	108.862	0.805	0.914	131.736	1	0.017
MV₆	8	0	55.751	0.707	0.941	12.785	1	0.323
MV₇	20	0	151.582	0.704	0.577	201.144	1	-0.329
MV₈	60	0	78.064	0.661	0.768	188.331	1	-0.485
MV₉	12	0	46.416	0.675	0.818	114.486	1	0.082
MV₁₀	8	0	46.231	0.977	0.95	95.321	1	0.260
MV₁₁	20	0	108.862	0.974	0.729	240.577	1	-0.251
MV₁₂	60	0	25.359	0.959	0.819	61.459	1	-0.032
MV₁₃	12	0	55.751	0.728	0.772	44.697	1	0.164
MV₁₄	8	0	46.231	0.66	0.806	53.966	1	0.214
MV₁₅	20	0	25.359	0.678	0.579	66.141	1	0.12

UAV 1: 16:45

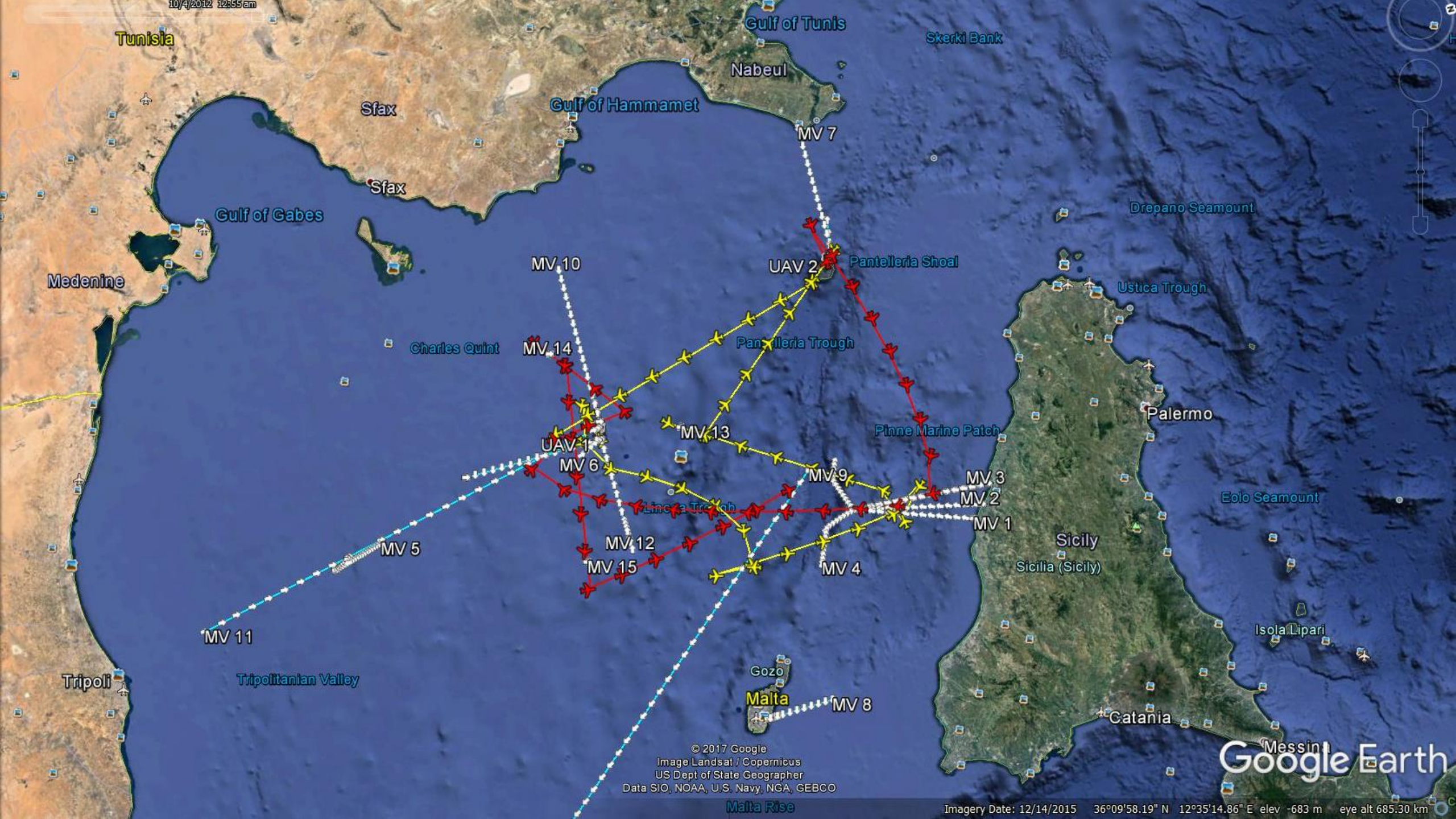
	C1	C2	C3	C4	C5	C6	C7	
Min/Max	MIN	MAX	MIN	MAX	MAX	MIN	MAX	
Pref. fn	Linear	Linear	Linear	Linear	Linear	Linear	Linear	
Preference	20	0.001	20	1	1	40	1	
Indifference	8	0	2	0	0	10	0	
Inflection	n/a	n/a	n/a	n/a	n/a	n/a	n/a	
Weight	0.139	0.104	0.062	0.069	0.184	0.084	0.358	<i>MV Ranking</i>
MV₁	12	0	9.043	0.691	0.685	197.567	1	-0.085
MV₂	8	0	9.043	0.973	0.551	201.404	1	-0.073
MV₃	20	0.037	11.01	0.977	0.578	195.009	1	0.073
MV₄	60	0.041	30.397	0.939	0.657	122.15	1	-0.129
MV₅	12	0	74.324	0.825	0.856	137.187	1	-0.072
MV₇	20	0	150.365	0.899	0.638	200.435	1	-0.361
MV₈	60	0	86.26	0.994	0.659	167.196	1	-0.554
MV₉	12	0.045	30.397	0.663	0.829	95.352	1	0.324
MV₁₀	8	0	36.624	0.975	0.699	101.887	1	0.059
MV₁₁	20	3.022	74.324	0.966	0.961	211.033	1	0.143
MV₁₂	60	0	26.623	0.949	0.821	37.293	1	-0.120
MV₁₃	12	0	47.851	0.728	0.77	43.98	1	0.086
MV₁₄	8	0	36.624	0.661	0.806	71.302	1	0.110
MV₁₅	20	0	26.623	0.678	0.579	52.574	1	0.024

Investigation of 15 MVs by 2 UAVs

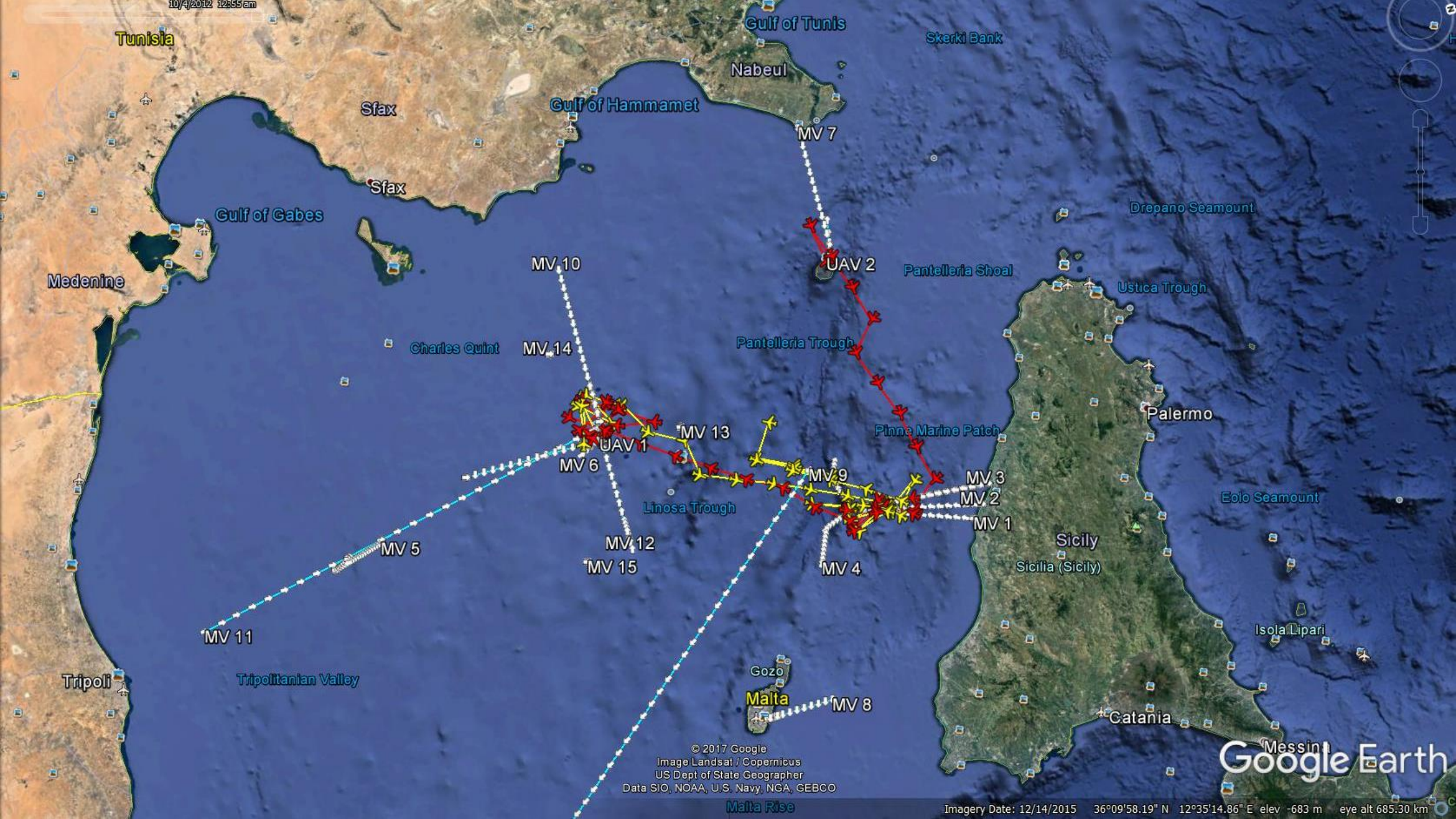


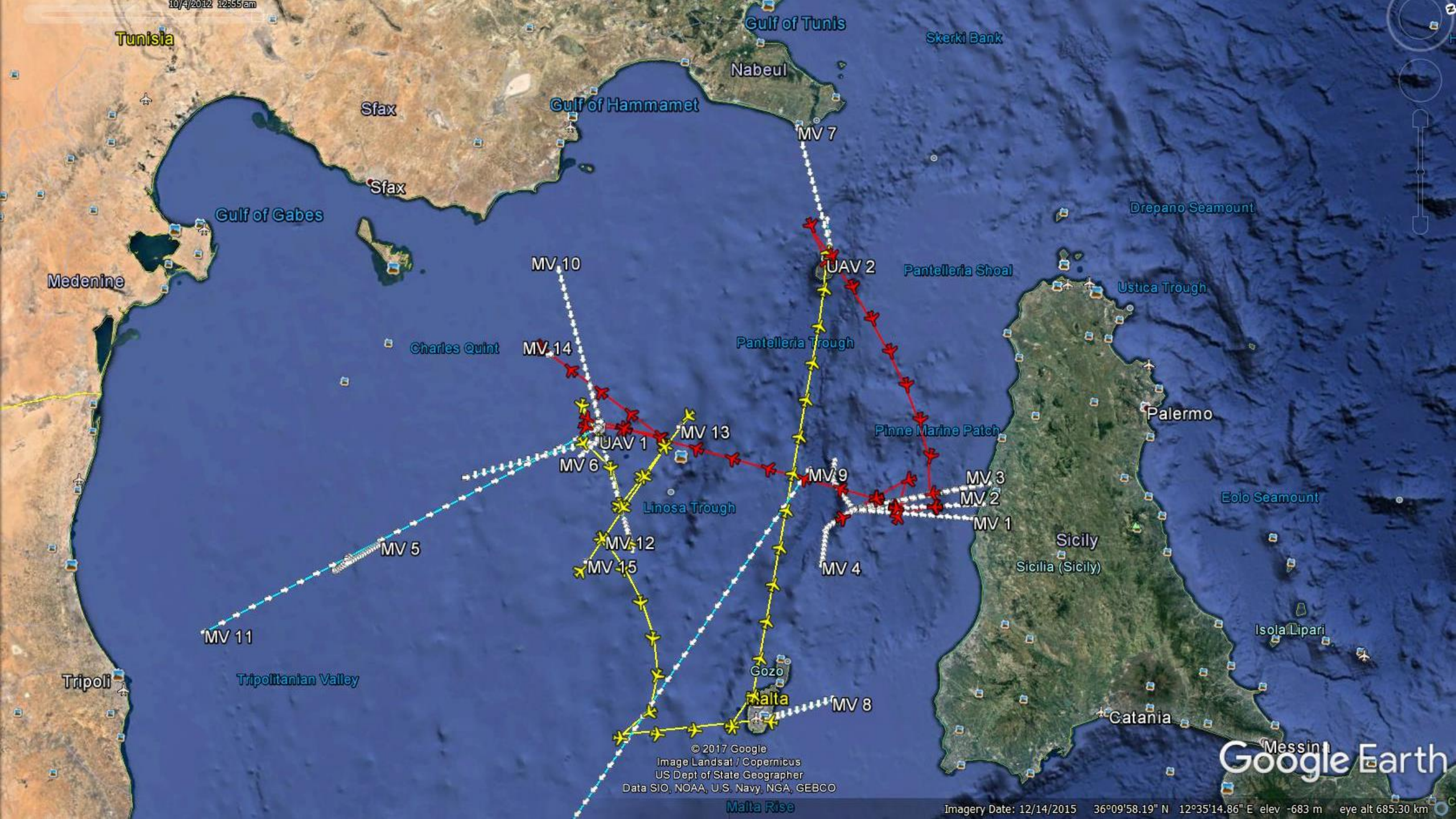
Time dependent autonomous / swarm autonomous systems

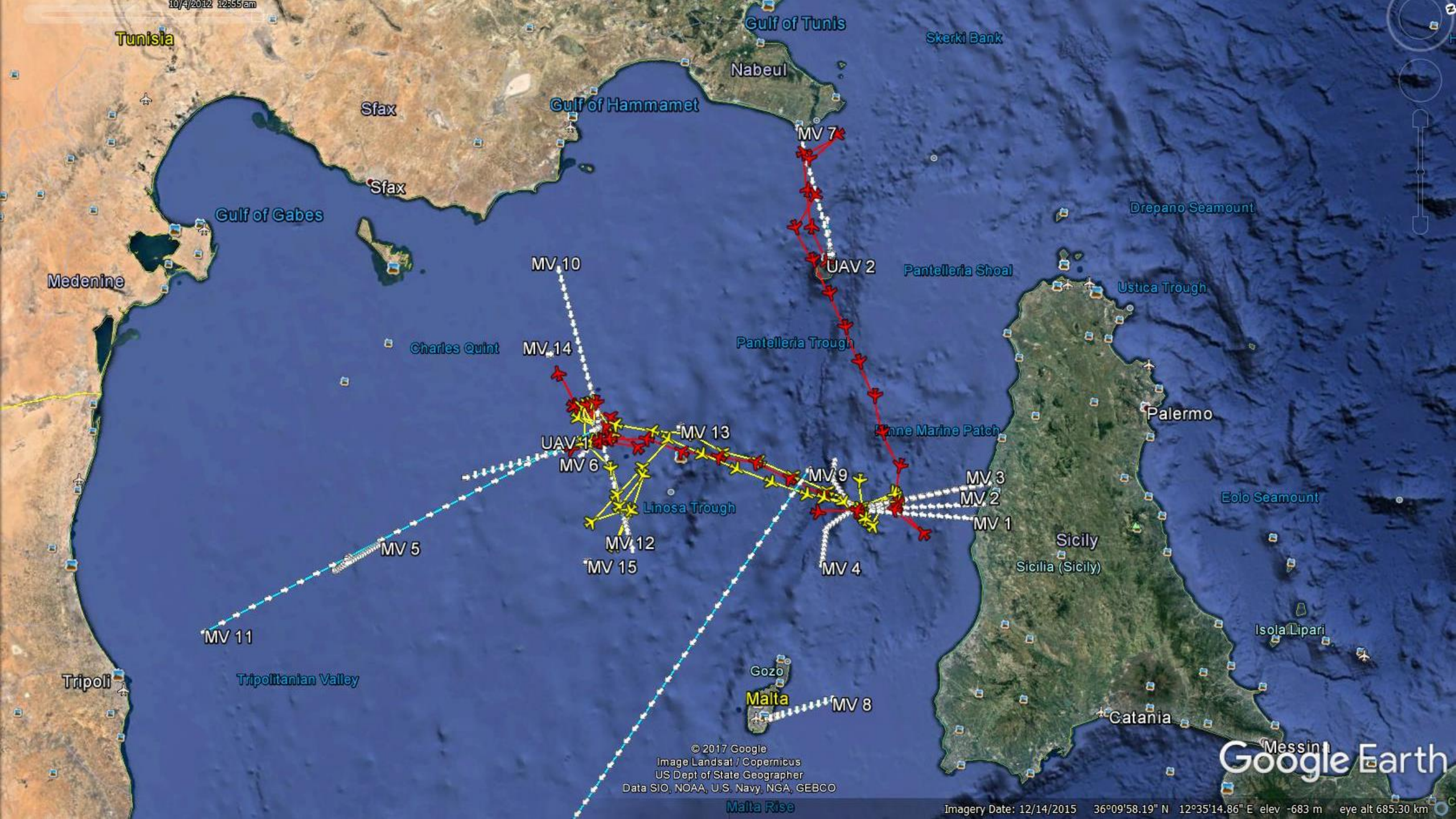
- The swarm autonomous simulation for a multicriteria (investigate and forget) system, can be seen on:
- <https://www.youtube.com/watch?v=WBrX-iQ9Uao>
- For a single autonomous simulation for a multicriteria (only investigate):
- https://www.youtube.com/watch?v=AS4_8Ej0otc
- An independent autonomous simulation for a multicriteria (only investigate) with mathematical programming:
- <https://www.youtube.com/watch?v=OUlg24xKsXI>
- The swarm autonomous simulation for a single criterion as minimum distance of UAV to MV (investigate and forget) system, can be seen on:
- <https://www.youtube.com/watch?v=QDSFMPYZdsc>
- An independent autonomous simulation for a single criterion as minimum distance of UAV to MV (only investigate):
- <https://www.youtube.com/watch?v=g9nVJTFwnx8>
- An independent autonomous simulation for a single criterion as minimum distance of UAV to MV (only investigate) with mathematical programming:
- https://www.youtube.com/watch?v=tD_EjGqe93w













Applications

Hazardous scene assessment

Last mile resupply

Aviation security



Questions?