

University Degree in Data Science and Engineering and  
Telecommunication Technologies Engineering  
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*Bachelor thesis*

# Applications of Autonomous Drones for Non-Terrestrial Networks in Remote Areas

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Leganés, 2025



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## **ABSTRACT**

this is an abstract

**Keywords:** keyword1, keyword2, keyword3



## **ACKNOWLEDGMENTS**

Thanks

## **AGRADECIMIENTOS**

Gracias



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## ACRONYMS

3G	3rd Generation.
4G	4th Generation.
5G	5th Generation.
AESA	Spanish Aviation Safety and Security Agency.
AI	Artificial Intelligence.
AI Act	Artificial Intelligence Act.
ANN	Artificial Neural Network.
CNN	Convolutional Neural Network.
DL	Deep Learning.
EASA	European Aviation Safety Agency.
EU	European Union.
FPV	First Person View.
GAN	Generative Adversarial Network.
GEO	Geostationary Earth Orbit.
HAP	High Altitude Platform.
INCOSE	International Council on Systems Engineering.
IoT	Internet of Things.
LEO	Low Earth Orbit.
LTE	Long-Term Evolution.
ML	Machine Learning.
MTOW	Maximum Takeoff Weight.
NTN	Non-Terrestrial Network.
RNN	Recurrent Neural Network.
SES	Single European Sky.
STP	Standard Temperature and Pressure.
STS	Standard Training Scenario.
UAS	Unmanned Aircraft System.
UAV	Unmanned Aerial Vehicle.
VLOS	Visual Line of Sight.



# **Part I**

## **Introduction**



## 1. MOTIVATION

**TODO:** write this chapter

## 2. STATEMENT OF THE PROBLEM

Current research in the domain of Non-Terrestrial Network (NTN) primarily focuses on the development of satellite constellations in Geostationary Earth Orbit (GEO) and Low Earth Orbit (LEO) [1]. While these satellites offer significant potential, their high costs and limited customizability render them impractical for many research groups and individual researchers. Moreover, the complexity of launching and maintaining satellites in orbit presents a significant barrier to entry for many interested parties. In contrast, drones present a more affordable and adaptable solution for rapid deployment of communication networks in remote areas as well as low-altitude surveillance and monitoring missions.

The core challenge addressed in this thesis is the lack of widely accessible solutions for the deployment of autonomous drones in remote areas. Presently, available solutions are either expensive, proprietary systems that lack customization, or they require extensive infrastructure, such as ground stations or high-speed internet connectivity. These requirements severely limit the application of drones in areas with minimal or no infrastructure.

This work seeks to address the gap by developing a comprehensive, open-source, and cost-effective solution for autonomous drone missions in remote environments. Given the broad nature of this problem, the scope of this thesis will be narrowed to a specific environment and use case, as outlined below:

- **Environment:** The modeled environment will be a remote area with minimal infrastructure, such as a forest, desert, or mountain. Specifically, the case study will involve an esplanade—a flat area devoid of significant obstacles like buildings or trees—allowing the drone to operate without the risk of collision. Moreover, 4th Generation (4G) or 5th Generation (5G) connectivity will be assumed to be available, enabling the drone to communicate with a ground station.
- **Atmospheric Conditions:** The selected environment will feature a clear sky, with minimal electromagnetic interference from other sources such as drones or aircraft. Additionally, the conditions will approximate Standard Temperature and Pressure (STP) of 15 °C and 1013 hPa.
- **Operational Parameters:** The drone operations will be confined to Visual Line of Sight (VLOS) and an altitude below 120 m, ensuring compliance with current aviation regulations in Spain and most countries. The Maximum Takeoff Weight (MTOW) of the drone will not exceed 25 kg.
- **Hardware:** The drone will be constructed using commercially available, off-the-shelf components to ensure affordability and ease of replication for other research groups and individuals.
- **Application:** This work will focus on the application of drones in human rescue missions, such as search and rescue operations in disaster-stricken areas or monitoring remote environments for signs of danger. While there are other potential applications of drones in remote areas, human rescue offers significant societal benefits.

### **3. OBJECTIVES**

The primary aim of this thesis is to provide the research community and humanitarian organizations with an open-source, modular, and customizable drone capable of operating in remote areas. The drone will be designed to be cost-effective, user-friendly, and competitive with other market offerings. It will incorporate the latest advancements in drone technology to ensure optimal performance and reliability.

In addition, a reconnaissance platform will be developed to enable the operation of the drone for scouting and observation tasks. The platform will support multiple drones, allowing for the deployment of a coordinated swarm to conduct surveillance and monitoring missions effectively. The software will be user-friendly, enabling researchers and humanitarian organizations to program the drones for specific tasks easily.

To achieve these objectives, the following specific aims will be pursued:

- The design must be modular and customizable, enabling easy modifications to adapt the drone for different applications.
- The components utilized in the drone should be off-the-shelf and readily available, facilitating straightforward assembly and repairs.
- The drone must be capable of autonomous flight to enable operations in remote areas where manual control is challenging.
- The design will incorporate the latest advancements in drone technology, ensuring competitiveness with other market offerings.
- The drone must be capable of communicating with a ground station to facilitate remote control.
- The reconnaissance platform should be programmable to perform specific tasks, such as reconnaissance of designated areas and monitoring of particular parameters.
- The reconnaissance platform must support multiple drones, allowing for the deployment of a coordinated swarm to conduct reconnaissance tasks effectively.

## 4. DOCUMENT STRUCTURE

**TODO:** Write this chapter when all the document is finished.

## 5. METHODOLOGICAL FRAMEWORK

The methodological framework employed in this thesis is grounded in the V-model as established by the International Council on Systems Engineering (INCOSE) [2] for project development. The V-model offers a rigorous and structured method that ensures all project facets are considered, facilitating timely and budget-compliant completion. This is achieved through a comprehensive development process, enabling clear validation and verification of initial requirements at every stage.

The methodology is segmented into seven key components which can be summarized as follows:

1. **Identification of User Requirements:** A detailed analysis of the problem statement is conducted to identify the primary issues and potential solutions. Moreover, the user requirements are defined to ensure that the proposed solution aligns with the objectives of the project.
2. **System Design:** The system architecture is developed based on the user requirements, ensuring that the proposed solution is feasible and aligns with the project's objectives. This phase includes a detailed overview of the system components and their interconnections. Requirements are formulated to satisfy the previously defined solution requirements. This phase includes a high-level overview of the components of the proposed solution, the justification for their selection, and the interconnections among them.
3. **Component Design:** Building upon the high-level architecture of the solution, a more detailed approach is outlined for each component, taking into account their specific power and data transmission needs. This culminates in a comprehensive architecture of the solution. Furthermore, a detailed overview of the components is provided, including the rationale for their selection and the interconnections among them.
4. **Implementation:** The proposed solution is implemented and manufactured utilizing available tools while simultaneously integrating the necessary electrical components. This phase includes a detailed description of the implementation process, including the tools and materials used, as well as the integration of electrical components. The development of software and hardware components is also detailed.
5. **Component Testing:** The functionality of each component is verified in a standalone mode, with detailed information provided regarding the verification process.
6. **System Testing:** The methodology for conducting flight tests and subsequent analyses is elaborated. System integration is performed by assessing communication between module pairs to ensure that data can be transmitted freely and utilized effectively.
7. **Acceptance Testing:** Validation of the initial requirements is conducted to confirm that all solution requirements have been met. This phase also includes preparations for potential future enhancements.

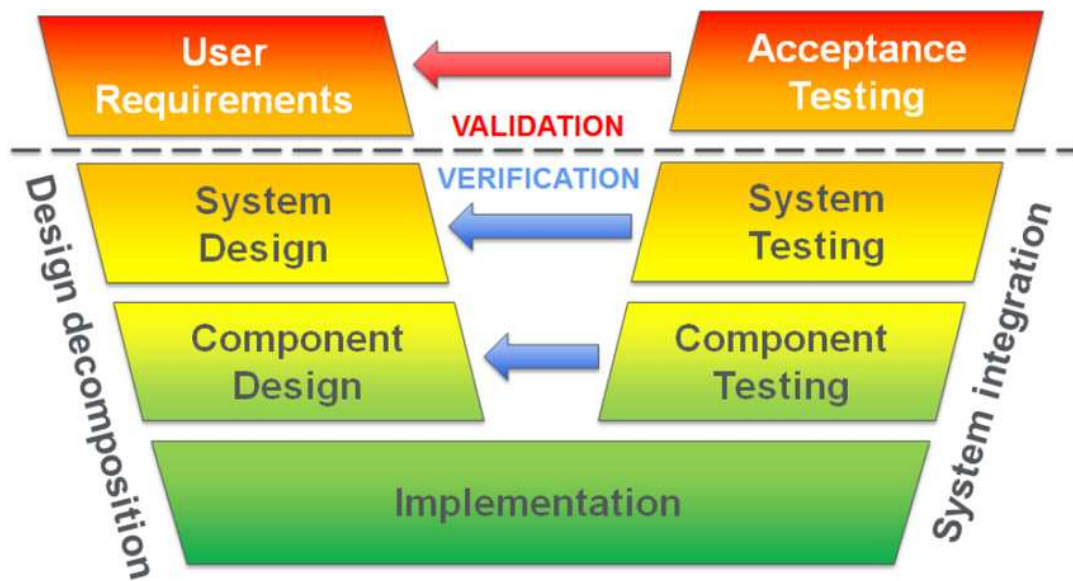


Figure 5.1. Methodological framework based on the V-model from INCOSE with the different stages of the project development process[3]

Moreover, a graphical representation of the V-model is provided in Figure 5.1 to illustrate the methodology's structure and the relationship between the various stages.



# **Part II**

## **Theoretical Background**



## 6. NON-TERRESTRIAL NETWORKS

NTNs represent a groundbreaking approach in wireless communication, utilizing aerial and space-based platforms to deliver connectivity services. These platforms can operate at varying altitudes, from a few hundred meters to several kilometers above ground, offering key advantages over traditional terrestrial networks, such as expanded coverage, increased capacity, and greater flexibility.

NTNs provide a promising solution to meet the rising demand for wireless access in remote and underserved areas. By leveraging aerial and space platforms, NTNs can extend the reach of conventional terrestrial networks, offering connectivity where traditional infrastructure is either difficult or impossible to deploy. These platforms are available in several configurations, including High Altitude Platforms (HAPs), LEO satellites, and GEO satellites, each with distinct benefits in terms of coverage, capacity, and latency, making them suitable for various use cases. In Figure 6.1, we illustrate the different types of NTNs based on altitude and platform type as well as their interaction with other network elements such as ground stations, Unmanned Aerial Vehicles (UAVs), Internet of Things (IoT) devices, etc.

### 6.1 Geostationary Satellites

GEO satellites operate at an altitude of approximately 35 786 km above the Earth's equator. These satellites maintain a fixed position relative to the Earth's surface, as they orbit at the same rate as the planet's rotation. GEO satellites offer extensive coverage, often spanning entire continents, and are widely used for telecommunications, broadcasting, and weather monitoring.

Compared to LEO satellites, GEO satellites offer broader coverage and higher capacity, making them ideal for applications like direct-to-home television, satellite radio, and broadband internet access. Their capacity to cover large regions makes GEOs integral to global communications infrastructure.

A key advantage of GEO satellites is their ability to support high-capacity services for many users, making them valuable for broadcasting live events, such as sports and concerts, or delivering high-definition video content worldwide. As a fundamental part of the global media and communication ecosystem, GEO satellites are expected to continue playing a vital role in providing connectivity to remote and underserved regions.

### 6.2 Low-Earth Orbit Satellites

LEO satellites operate at altitudes between 160 km and 2000 km above the Earth. Orbiting at high speeds, these satellites provide global coverage, making them ideal for delivering connectivity to remote and underserved regions. LEO satellites offer several advantages over traditional GEO satellites, including lower latency, higher capacity, and reduced infrastructure costs.

Deployed in constellations consisting of hundreds or thousands of satellites, LEO satellites work together to provide continuous coverage. These satellites communicate through inter-satellite links, allowing data to be relayed seamlessly across the constellation. LEO

satellites are well-suited for delivering broadband internet access in areas where traditional infrastructure is difficult to establish.

One of the primary advantages of LEO satellites is their low latency, enabling real-time communication and supporting applications that require minimal delay, such as online gaming, video conferencing, and autonomous vehicle systems. Additionally, LEO satellites offer high-speed internet connectivity to users in remote locations, granting access to online services, educational platforms, and e-commerce opportunities. As a critical part of the emerging NTN ecosystem, LEO satellites are expected to play a key role in bridging the global digital divide.

### **6.3 High-Altitude Platforms**

HAPs operate at altitudes ranging from a few hundred meters to several kilometers above the Earth. These platforms may consist of balloons, airships, or UAVs. They provide several benefits compared to traditional terrestrial networks, including broader coverage, increased capacity, and lower infrastructure costs. HAPs can be deployed swiftly to offer connectivity in remote or underserved areas, making them an effective tool for reducing the digital divide.

Additionally, HAPs can provide temporary connectivity in disaster-stricken regions or during large-scale events. Rapid deployment allows emergency responders to coordinate efforts efficiently. They can also extend the coverage of existing networks in rural areas, where conventional infrastructure is costly or challenging to install.

Advances in UAV technology have enabled the development of autonomous HAPs equipped with Long-Term Evolution (LTE) or 5G base stations, flying at altitudes of up to 20 km. These platforms cover vast areas and support a range of applications, making them ideal for remote and underserved locations where deploying traditional infrastructure is not practical.

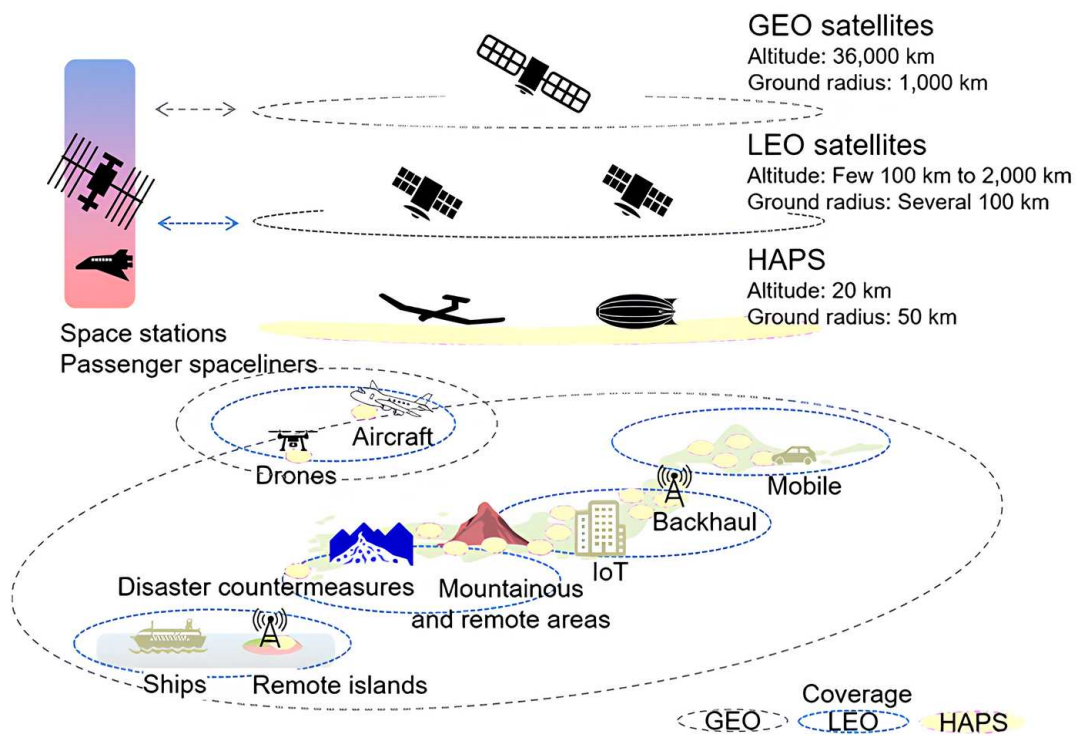


Figure 6.1. Types of NTNs based on altitude and platform type. HAPs, LEOs satellites, and GEOs satellites interact with other network elements to provide connectivity services. [4]

## 7. UNMANNED AERIAL VEHICLES

The term UAV encompasses a diverse range of aircraft, from compact quad-copters to larger fixed-wing models. What primarily distinguishes UAVs from conventional aircraft is that UAVs are either remotely piloted or autonomously controlled, whereas traditional aircraft are operated by human pilots. This autonomy enables UAVs to be deployed in scenarios where human presence is either impractical or hazardous, such as military operations or environments with significant risk.

UAVs serve various purposes across multiple industries, including surveillance, reconnaissance, search and rescue missions, and scientific research. Additionally, they have become invaluable in sectors like agriculture, forestry, and environmental monitoring. In recent years, UAVs have gained popularity among hobbyists for recreational flying and personal projects.

### 7.1 Types of Unnamed Aerial Vehicles

In line with the classification presented by the European Aviation Safety Agency (EASA) [5], UAVs can be categorized into three main types, each based on size, weight, physical design, and operational capabilities:

- **Fixed-wing UAVs:** These aircraft feature fixed wings and function similarly to conventional airplanes. They tend to be larger and designed for long-duration flights, making them suitable for extended missions like surveillance, reconnaissance, and mapping. However, they require runways for takeoff and landing, and cannot hover in place, limiting their versatility in confined spaces.
- **Rotary-wing UAVs:** Equipped with multiple rotors, these UAVs can take off and land vertically. They are typically smaller and more agile, making them ideal for close-range missions like aerial photography, search and rescue, and surveillance. However, their limited range and endurance compared to fixed-wing UAVs restrict their use in long-duration missions.
- **Hybrid UAVs:** Combining the features of both fixed-wing and rotary-wing designs, hybrid UAVs can take off and land vertically like rotary-wing models while achieving greater range and endurance through fixed-wing flight. These aircraft are ideal for missions requiring versatility, such as reconnaissance and mapping. Despite their advantages, they are more complex and costly to operate than single-type UAVs.

Figure 7.1 illustrates the different UAVs types based on their design and intended applications.

In Table 7.1, a detailed comparison of fixed-wing, rotary-wing, and hybrid UAVs is presented across various performance metrics, including size, range, endurance, cost, and ease of operation. The table provides insights to help in selecting the appropriate UAV for specific mission requirements, depending on factors like payload, range, and maneuverability.

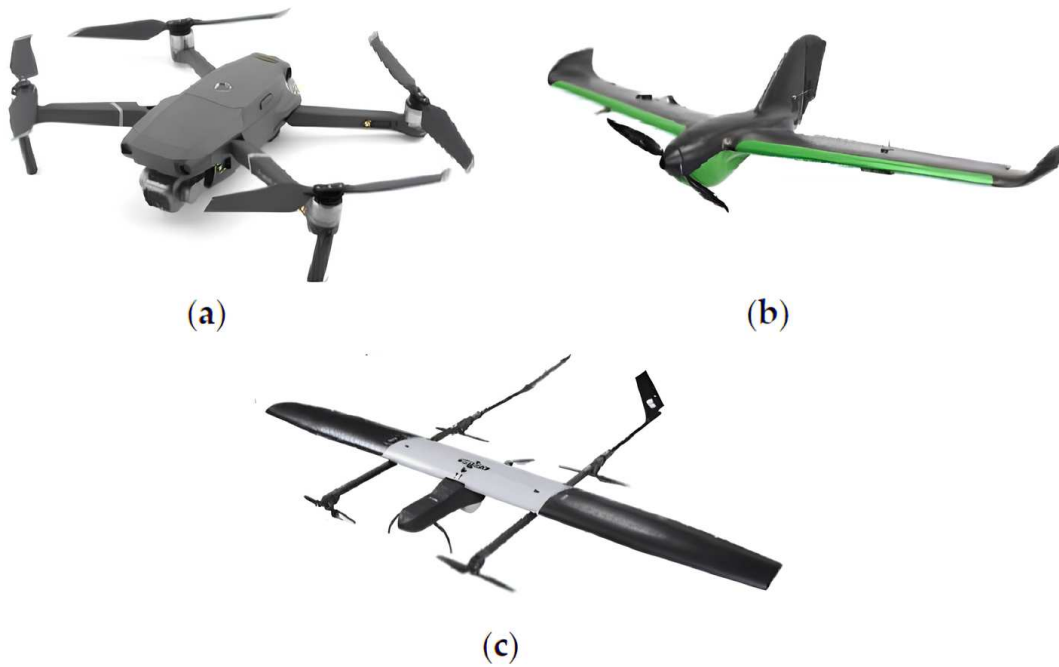


Figure 7.1. Types of UAVs based on their design and intended use [6]. a. Rotary-wing UAV, b. Fixed-wing UAV, c. Hybrid UAV

Metric	Fixed-wing	Rotary-wing	Hybrid
Size	Moderate	Small	Large
Range	Long	Short	Moderate
Endurance	High	Low	Moderate
Payload capacity	High	Low	Moderate
Maneuverability	Low	High	Moderate
Ease of use	Moderate	High	Low
Maintenance	Moderate	Low	High
Runway requirement	Yes	No	Yes
Cost	Moderate	Low	High

Table 7.1. Comparison of fixed-wing, rotary-wing, and hybrid UAVs across various performance metrics

## 7.2 Applications of Unmanned Aerial Vehicles

UAVs have a wide range of applications across different industries, leveraging their versatility, maneuverability, and autonomy. Some common applications of UAVs include:

- **Aerial photography and videography:** UAVs equipped with high-resolution cameras are used for capturing aerial images and videos for various purposes, including filmmaking, real estate, and landscape photography.
- **Agriculture:** UAVs are employed in precision agriculture to monitor crop health, assess soil conditions, and optimize irrigation and fertilization practices. They can provide valuable insights to farmers for improving crop yield and reducing resource wastage.
- **Search and rescue:** UAVs equipped with thermal imaging cameras and other sensors are used in search and rescue operations to locate missing persons, assess disaster-affected areas, and deliver essential supplies to remote locations.
- **Infrastructure inspection:** UAVs are utilized for inspecting critical infrastructure like bridges, power lines, and pipelines. They can access hard-to-reach areas and capture detailed images for assessing structural integrity and identifying maintenance needs.
- **Environmental monitoring:** UAVs are deployed for monitoring environmental parameters like air quality, water quality, and wildlife populations. They can collect data in remote or hazardous environments, providing valuable insights for conservation efforts and scientific research.
- **Disaster response:** UAVs play a crucial role in disaster response by providing real-time situational awareness, mapping affected areas, and coordinating emergency operations. They can assist in assessing damage, locating survivors, and delivering aid to disaster-stricken regions.
- **Military and defense:** UAVs are extensively used in military and defense applications for reconnaissance, surveillance, target acquisition, and combat operations. They offer a cost-effective and low-risk alternative to manned aircraft in high-risk environments.
- **Delivery services:** UAVs are increasingly being used for last-mile delivery of goods and services. Companies like Amazon and UPS are exploring the use of UAVs for delivering packages to customers in urban and rural areas.

## 8. DEEP LEARNING

Deep Learning (DL) is a subfield of Machine Learning (ML) that focuses on the development of algorithms and models inspired by the structure and function of the human brain. These algorithms are designed to learn from data, identify patterns and relationships, and make predictions or decisions without explicit instructions. DL algorithms are characterized by their ability to automatically discover and extract features from raw data, enabling them to perform complex tasks such as image recognition, speech recognition, and natural language processing.

DL has revolutionized various industries and domains, including healthcare, finance, transportation, and entertainment. By leveraging the power of DL, organizations can analyze large datasets, extract valuable insights, and automate complex tasks, leading to improved decision-making, enhanced user experiences, and optimized processes. From self-driving cars and virtual assistants to medical diagnostics and fraud detection, DL is transforming the way we interact with technology and the world around us.

Furthermore, DL plays a crucial role in enabling UAV autonomy, allowing drones to perform tasks such as navigation, obstacle avoidance, and object recognition without human intervention. By integrating DL algorithms into UAV systems, researchers and developers can enhance the capabilities and efficiency of drones, enabling them to operate in complex environments and execute sophisticated missions.

### 8.1 Deep Learning Techniques

DL encompasses a wide range of techniques and architectures that enable machines to learn from data and make decisions. Some of the most common DL techniques include:

- **Artificial Neural Network (ANN):** ANN are computational models inspired by the structure and function of the human brain. They consist of interconnected nodes, or neurons, organized in layers, with each neuron performing a simple computation. ANN can learn complex patterns and relationships in data through a process called back-propagation, where errors are propagated back through the network to adjust the model's parameters. ANN are used in a variety of tasks, such as classification, regression, and clustering.
- **Convolutional Neural Network (CNN):** CNN are a type of ANN designed for processing and analyzing visual data, such as images and videos. They use convolutional layers to extract features from input data, pooling layers to reduce spatial dimensions, and fully connected layers to make predictions. CNN are widely used in image recognition, object detection, and image segmentation tasks.
- **Recurrent Neural Network (RNN):** RNN are a type of ANN designed for processing sequential data, such as time series, text, and speech. They have feedback connections that allow information to persist over time, enabling them to capture temporal dependencies in data. RNN are used in natural language processing, speech recognition, and machine translation tasks.
- **Generative Adversarial Network (GAN):** GAN are a type of DL model that consists of two neural networks, a generator and a discriminator, trained adversari-

ally. The generator generates synthetic data samples, while the discriminator distinguishes between real and fake samples. GAN are used in image generation, style transfer, and data augmentation tasks.

These techniques form the foundation of DL and are used in a wide range of applications across various domains, enabling machines to perform complex tasks and make intelligent decisions. In the context of NTN and UAVs, DL techniques can enhance network performance, optimize resource allocation, and enable autonomous operation, leading to more efficient and reliable systems. Furthermore, DL can enable UAVs to perform tasks such as navigation, object detection, and mission planning with high accuracy and efficiency, making them valuable tools for a wide range of applications (e.g., surveillance, monitoring, and disaster response).





## **Part III**

### **State of the art**

## 9. HISTORICAL DEVELOPMENT

**TODO:** write this chapter

## 10. TYPES & TECHNOLOGIES

**TODO:** write this chapter

## 11. MODERN TRENDS

**TODO:** write this chapter

## **12. REGULATORY FRAMEWORK**

The regulatory framework governing drones is a complex and dynamic area, influenced by various laws and regulations that differ from country to country. Generally, drone operations are regulated by aviation authorities responsible for ensuring safe and responsible usage.

### **12.1 Relevant Institutions**

#### **12.1.1 European Union Aviation Safety Agency (EASA)**

The EASA [7] plays a crucial role in harmonizing aviation safety standards across all European Union (EU) member states. Its primary objective is to maintain a consistent and high level of safety in civil aviation operations throughout the EU. EASA achieves this through the establishment and enforcement of common regulations applicable to all member states. Notably, for the standardization of Unmanned Aircraft System (UAS), EASA has implemented Regulations (EU) 2019/947 [5] and (EU) 2019/945 [8].

#### **12.1.2 State Aviation Safety Agency (AESA)**

In Spain, the Spanish Aviation Safety and Security Agency (AESA) [9] serves as the national regulatory authority, overseeing compliance with civil aviation standards within the aerospace sector. AESA plays a critical role in promoting the development and application of aviation legislation, ensuring that the Spanish civil aviation system upholds the highest safety, quality, and sustainability standards. In instances of non-compliance with aviation regulations, AESA possesses the authority to enforce sanctions.

### **12.2 Applicable Legislation**

#### **12.2.1 Implementing Regulation (EU) 2019/947**

The Implementing Regulation (EU) 2019/947 [5] establishes the operational rules and requirements for UAS within the EU. It provides a legal framework for the utilization of UAS across various operational categories, outlining requirements for operational authorizations and risk assessments where applicable. The regulation sets standards for remote pilot competency, operational procedures, and safety management to conduct UAS flights safely and effectively.

Additionally, it integrates with the Delegated Regulation (EU) 2019/945 [8] by defining operational requirements related to the UAS classes established within it. The regulation details specific operational limitations and conditions for each UAS class, including the management of UAS in classes C0 through C4. It also includes provisions for the safe integration of newly introduced UAS classes under Delegated Regulation (EU) 2020/1058 [10], specifically classes C5 and C6.

Moreover, this regulation addresses the procedures for UAS operators from third countries (non-EASA member states) wishing to operate within the Single European Sky (SES) airspace, ensuring alignment with EU standards and safety regulations.

### 12.2.2 Delegated Regulation (EU) 2019/945

The Delegated Regulation (EU) 2019/945 [8] defines the rules and standards for UAS within the EU. It specifies the types of UAS that require certification regarding design, production, and maintenance. This regulation also provides guidelines for the commercialization of UAS intended for use in the Open category, as well as for remote identification accessories (e.g., Drone Remote ID). Furthermore, it outlines the requirements for the design and manufacture of UAS intended for operations defined in the Implementing Regulation (EU) 2019/947.

### 12.2.3 Regulation (EU) 2024/1689: Artificial Intelligence Act

The Artificial Intelligence Act (AI Act) of the EU [11], which came into force on the 1st of August 2024, aims to ensure that Artificial Intelligence (AI) systems are safe, transparent, and ethical, while fostering innovation and protecting fundamental rights as stated in the Delegated Regulation (EU) 2024/1689 [12]. The AI Act categorizes AI systems by risk, imposing strict requirements on high-risk applications, particularly in aviation, which may affect public safety and fundamental rights. These requirements encompass robust risk management, transparency, human oversight, and data governance, ensuring that AI systems are reliable and secure.

The AI Act introduces significant compliance obligations that could escalate development costs and timelines. High-risk systems must adhere to stringent standards to access the EU market, potentially challenging innovation but ultimately aiming to build trust and facilitate broader adoption of AI technologies within the EU.

## 12.3 Operational Categories

The Regulation (EU) 2019/947 [5] classifies UAS into three distinct categories:

- **Open Category:** The least restrictive category, designed for low-risk operations, includes activities such as recreational flying and commercial operations posing minimal risk to people and property. Operators must adhere to specific limitations (e.g., flying below 120 meters, maintaining VLOS). UAS must weigh under 25 kg, and pilots must ensure that the drone does not fly over people or in restricted areas. No prior authorization is required, though registration and remote pilot training are compulsory for all operations, except for drones weighing less than 250 g that lack a camera or sensor.
- **Specific Category:** This category covers medium-risk operations necessitating a more detailed assessment. It includes operations that may involve flying over people or in restricted areas, provided mitigation procedures are in place. Operators must conduct a risk assessment and obtain an operational authorization known as Standard Training Scenario (STS) from AESA. Requirements for UAS and pilot qualifications may vary based on the specific risk assessment and operational procedures defined within it.
- **Certified Category:** Designed for high-risk operations, this category involves stringent requirements comparable to those for manned aviation. UAS must meet specific certification standards and operators must comply with strict safety regulations. This category often includes advanced training requirements and operational procedures similar to those for commercial air transport.

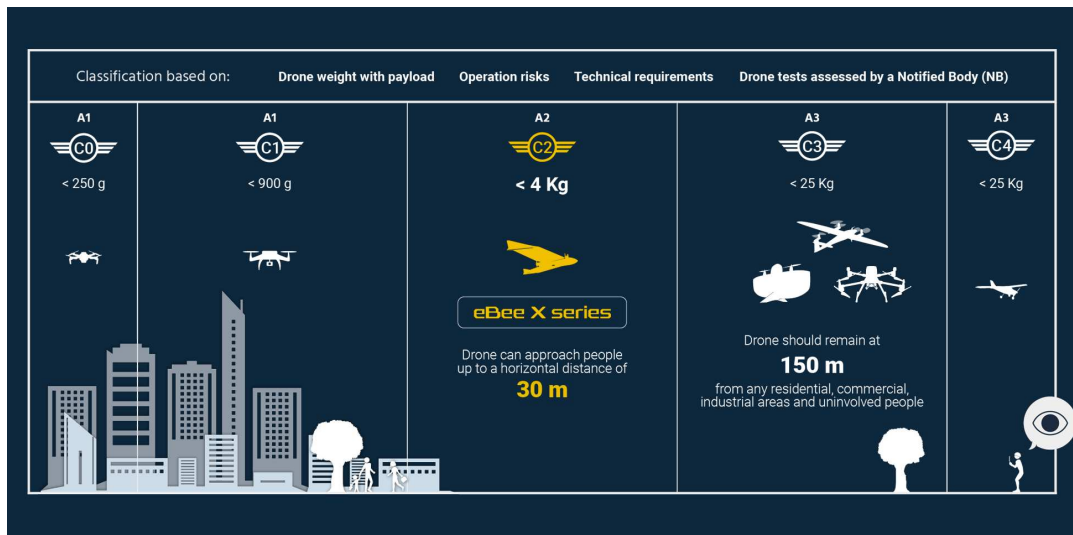


Figure 12.1. *EU Regulations Open Category chart describing the subcategories A1, A2, and A3 with their respective operational limitations [13]*

### 12.3.1 Open Category

This work will focus on civil UAS that fall under EASA’s Open Category, although some findings may be applicable to other categories with appropriate regulatory adjustments. Within the Open Category, three subcategories differentiate based on associated risk, aircraft weight, and operational limits:

1. **A1:** UAS with a MTOW of less than 250 g that can fly over people but not over assemblies of people.
2. **A2:** UAS with an MTOW of less than 4 kg that can fly close to people but must maintain a horizontal distance of 30 meters (5 meters in low-speed configuration).
3. **A3:** UAS with an MTOW of less than 25 kg that must maintain a horizontal distance of 150 meters from residential, commercial, industrial, or recreational areas.

Check Figure 12.1 for a visual representation of the Open Category subcategories.

Moreover, additional rules applicable to all three subcategories include:

- The maximum height must not exceed 120 meters above ground level, as the lower limit for general aviation is 150 meters. This leaves only a 30-meter separation between manned aviation and UAS.
- Operators must always maintain VLOS unless the aircraft is in “follow me” mode or the pilot is using First Person View (FPV) goggles.
- Operators must register if the UAS weighs more than 250 g or if the aircraft is equipped with a camera or sensor.
- The aircraft must possess a remote identification ID, which is standard in all C1-C6 categories, with the exception of C4 and privately built aircraft.





# **Part IV**

## **Methodology**

## **13. REQUIREMENTS**

Based on careful analysis of the conclusions from the current trends in UAVs outlined in Chapter 11 and the objectives reviewed in Chapter 3, the following requirements are established for the high-level system as well as the detailed requirements for the UAV, control station, and reconnaissance platform.

### **13.1 High-level System Requirements**

The high-level system requirements are as follows:

- The system must be able to operate in remote areas with limited infrastructure, such as roads, electricity, and internet connectivity.
- The system must be able to be monitored remotely, with the ability to communicate with a ground station via a 4G or 3rd Generation (3G) connection.
- The system must be cost-effective, with the ability to be assembled and disassembled easily, and to be repaired and maintained with minimal effort.
- The system must be modular, allowing for the integration of different sensors and payloads for different applications, as well as, the scalability of the system to include multiple UAVs working together in a coordinated manner.
- The system must be able to perform reconnaissance tasks autonomously, with the ability to take off, land, and navigate given a set of waypoints.
- The system must comply with the applicable regulatory framework for UAVs in the country of operation, Spain, as well as the EU regulations. See Chapter 12 for more information.

### **13.2 Unmanned Aerial Vehicle Requirements**

The UAV requirements are as follows:

- The UAV must be able to be controlled remotely, with the ability to communicate with a ground station in real-time.
- The UAV must be able to take off, land, and navigate autonomously, with the ability to update its flight plan in real-time.
- The UAV must be able to process data in real-time, with the ability to relay the information to the ground station.
- The UAV must be able to carry different payloads and sensors for different applications up to a maximum payload weight of 2 kg, with the ability to adapt to different reconnaissance tasks.
- The UAV must be able to fly for a minimum of 30 minutes, without the need for recharging.
- The UAV must have a failsafe mechanism, that is it must be able to return to the ground station in case of loss of communication or other critical failures.

- The UAV must be able to keep a fixed altitude and position.
- The UAV must comply with the EASA regulations for the Open Category, with a maximum limit set at 25 kg of MTOW and 3 meters of wingspan.
- The UAV must be able to perform reconnaissance tasks, such as mapping, surveillance, and monitoring the environment.

### 13.3 Control Station Requirements

The control station requirements are as follows:

- The control station must be able to receive telemetry data from the UAV in real-time, with the ability to send commands to the UAV to update its flight plan.
- The control station must be able to be used remotely, with the ability to communicate with the UAV via a 4G or 3G connection.
- The control station must be able to create a geofence around the area of operation, with the ability to monitor the UAV's position and altitude in real-time.
- The control station must have the capability be able to track multiple UAVs simultaneously, with the ability to coordinate their flight plans and tasks.
- The control station must log all telemetry data and flight information, with the ability to analyze the data and generate reports.

### 13.4 Reconnaissance Platform Requirements

The reconnaissance platform requirements are as follows:

- The reconnaissance platform must be able to run on a variety of operating systems, with the ability to communicate with the UAVs and the control station in real-time.
- The reconnaissance platform must be able to be used remotely, with the ability to access the UAVs and the control station via a 4G or 3G connection.
- The reconnaissance platform must be reliable, secure, and easy to use, allowing for the programming of the UAVs to perform specific tasks and the coordination of multiple UAVs in a swarm.
- The reconnaissance platform must be customizable, allowing for the integration of new features and the modification of existing ones, as well as, the addition of new UAVs to the system and different types of reconnaissance tasks.
- The reconnaissance platform must have alerting and notification capabilities, with the ability to send alerts and notifications to the user in case of critical events or failures.
- The reconnaissance platform must have a user-friendly interface, with the ability to display telemetry data and flight information in real-time, as well as, the ability to monitor the UAVs in real-time.

## 14. DESIGN

For the design of the system, the requirements defined in the Chapter 13 are taken into account. The system is divided into three main components: the UAV, which is the drone that performs the reconnaissance tasks, the ground station, which is the control station that monitors the UAV in real-time, the reconnaissance platform, which is the system that processes the data collected by the UAV and provides insights to the end-user, and the communication system, which is the system that allows the UAV to communicate with the ground station in real-time and also provides the connection to the reconnaissance platform.

### 14.1 Unmanned Aerial Vehicle

For the UAV design, the following components are considered: the airframe, the propulsion system, the flight controller, the power system, peripherals, and the payload.

#### 14.1.1 Airframe

The airframe is the structure of the UAV that holds all the components together. The airframe must be lightweight, durable, and easy to assemble and disassemble. The airframe must also be able to carry the payload and sensors required for the reconnaissance tasks.

For the airframe, different designs are considered, such as fixed-wing, rotary-wing, and hybrid designs as stated in Section 7.1. As one of the main requirements is the ability to take off and land in remote areas with limited infrastructure, a rotary-wing design is chosen for the UAV. The rotary-wing design allows for vertical takeoff and landing, as well as the ability to hover in place, which is useful for reconnaissance tasks.

Rotary-wing designs are further divided into multirotor and single-rotor designs as seen in **TODO: ref fig**. Multirotor designs are more stable and easier to control, while single-rotor designs are more efficient and have a longer flight time. For the UAV design, a quadcopter design is chosen, as it provides a good balance between stability and efficiency.

**TODO: add image of two types of airframes multirotor and single rotor**

For the material of the airframe, a lightweight and durable material is chosen, such as carbon fiber or aluminum. The airframe is designed to be modular, allowing for the integration of different sensors and payloads for different applications. The airframe is also designed to be scalable, allowing for the integration of multiple UAVs working together in a coordinated manner. And finally, the airframe is designed to be cost-effective and commercially available, with the ability to be assembled and disassembled easily, and to be repaired and maintained with minimal effort.

For that case the airframe chosen **TODO: add ref to where we bought it** is the **TODO: add which one**. It is a quadcopter design made of carbon fiber, with a wingspan of **TODO: add size** and a maximum takeoff weight of **TODO: add weight**. The airframe is designed to carry a maximum payload weight of **TODO: add weight**, with the ability to adapt to different reconnaissance tasks. Moreover, it has a payload bay that allows for the integration of different sensors and payloads, such as cameras, lidar, and thermal imaging sensors.

**TODO:** add image of the aireframe chosen

### 14.1.2 Propulsion System

The propulsion system is the system that provides the thrust required for the UAV to take off, land, and navigate. The propulsion system can be of different types, such as electric, gasoline, or hybrid. Electric propulsion systems are usually chosen for UAVs due to their efficiency, reliability, and low maintenance requirements. Gasoline propulsion systems are usually chosen for larger UAVs that require longer flight times and higher payloads. Hybrid propulsion systems are usually chosen for UAVs that require both efficiency and long flight times.

For the UAV design, an electric propulsion system is chosen, as it provides a good balance between efficiency, reliability, and low maintenance requirements. The electric propulsion system consists of four brushless motors, four electronic speed controllers, and four propellers. The main requirements of the propulsion system are the ability to provide enough thrust for the UAV to take off, land, and navigate, as well as the ability to carry the maximum payload weight of **TODO: add weight**.

The brushless motors chosen were the **TODO: add ref to where we bought them**, with a maximum thrust of **TODO: add thrust** and a maximum power of **TODO: add power**. The electronic speed controllers chosen were the **TODO: add ref to where we bought them**, with a maximum current of **TODO: add current** and a maximum voltage of **TODO: add voltage**. The propellers chosen were the **TODO: add ref to where we bought them**, with a maximum diameter of **TODO: add diameter** and a maximum pitch of **TODO: add pitch**. This complete propulsion system is designed to provide a thrust-to-weight ratio of **TODO: add ratio**, with the ability to carry the maximum payload weight of **TODO: add weight** which meets the requirements of the UAV design.

The system is designed to be modular, allowing for the integration of different propulsion systems for different applications. The system is also designed to be scalable, allowing for the integration of multiple UAVs working together in a coordinated manner. And finally, the system is designed to be cost-effective and commercially available, with the ability to be assembled and disassembled easily, and to be repaired and maintained with minimal effort.

**TODO:** add image of the propulsion system chosen

### 14.1.3 Flight Controller

The flight controller is the system that controls the UAV during flight. The flight controller is responsible for stabilizing the UAV, controlling the motors, and navigating the UAV to a set of waypoints. The flight controller can be of different types, such as manual, semi-autonomous, or autonomous. Manual flight controllers are usually chosen for UAVs that require human intervention during flight. Semi-autonomous flight controllers are usually chosen for UAVs that require human intervention for takeoff and landing, but can navigate autonomously to a set of waypoints. Autonomous flight controllers are usually chosen for UAVs that can take off, land, and navigate autonomously to a set of waypoints. One key feature of the flight controller is the *Return to Home* feature, which allows the UAV to return to the ground station in case of loss of communication or other critical failures.

For the UAV design, an autonomous flight controller is chosen, as it provides the ability to

take off, land, and navigate autonomously to a set of waypoints. Commercially, there are multiple flight controllers available **TODO: ref to table** and any of them can be used for the UAV design. The main requirements of the flight controller are the ability to stabilize the UAV, control the motors, and navigate the UAV to a set of waypoints, as well as the ability to communicate with the ground station in real-time. The flight controller chosen was the **TODO: add ref to where we bought it**, as **TODO: add reasons**. An image of the flight controller is shown in **TODO: add ref to fig**.

**TODO: add table of flight controllers**

**TODO: add image of the flight controller chosen**

#### 14.1.4 Power System

The power system is the system that provides the power required for the UAV to operate. The power system can be of different types, such as batteries, fuel cells, or solar panels. For UAVs, usually batteries are chosen, as they provide a good balance between energy density, power density, and weight. The main requirements of the power system are the ability to provide enough power for the UAV to take off, land, and navigate, as well as the ability to carry the maximum payload weight of **TODO: add weight**.

For the UAV design, a lithium polymer battery is chosen, as it provides a good balance between energy density, power density, and weight. The battery chosen was the **TODO: add ref to where we bought it**, with a maximum capacity of **TODO: add capacity** and a maximum voltage of **TODO: add voltage**. The battery is designed to provide enough power for the UAV to take off, land, and navigate, as well as the ability to carry the maximum payload weight of **TODO: add weight**. The battery is also designed to be modular, allowing for the integration of different batteries for different applications.

**TODO: add image of the power system chosen**

Moreover, usually the power system is divided into two parts, the power distribution system for the propulsion system and the power management system for the electronics. The main reason for this distinction is that the propulsion system requires a high current and low voltage, while the electronics require a low current and high voltage. However, for the UAV design, the power system is integrated into a single system to reduce weight and complexity and specially the pricing of the system.

Futhermore, in order to provide the required power for the different components of the UAV, a power management system is integrated into the power system. The power management system consists of a battery monitor, a voltage regulator, and a current sensor. The one chosen was the **TODO: add ref to where we bought it**, with a maximum current of **TODO: add current** and a maximum voltage of **TODO: add voltage**. The power management system is designed to provide the required power for the different components of the UAV, as well as the ability to monitor the battery voltage and current in real-time.

**TODO: add image of the power management system chosen**

#### 14.1.5 Peripherals

The peripherals are the components that provide additional functionality to the UAV. The peripherals can be of different types, such as sensors, geo-location systems, cameras, lidar, or thermal imaging sensors. For reconnaissance tasks, usually sensors and cameras are

chosen, as they provide the ability to collect data and images of the environment. The main requirements of the peripherals are the ability to collect data and images of the environment, as well as the ability to relay the information to the ground station in real-time.

For the UAV design, a module was integrated into the UAV, as it provides the ability to navigate the UAV to a set of waypoints. The module chosen was the **TODO: add ref to where we bought it**, with a maximum accuracy of **TODO: add accuracy** and a maximum update rate of **TODO: add rate**. The module is designed to provide the ability to navigate the UAV to a set of waypoints, as well as the ability to relay the information to the ground station in real-time. An image of the module is shown in **TODO: add ref to fig**.

**TODO: add image of the gps module chosen**

#### 14.1.6 Payload

The payload is the system that carries the sensors and cameras required for the reconnaissance tasks. The payload can be of different types, such as cameras, lidar, thermal imaging sensors, or multispectral sensors. For the UAV design, a camera is chosen, as it provides the ability to collect images of the environment. The main requirements of the payload are the ability to carry the sensors and cameras required for the reconnaissance tasks, as well as the ability to relay the information to the ground station in real-time.

For the UAV design, a camera was integrated into the UAV, as it provides the ability to collect images of the environment. The camera chosen was the **TODO: add ref to where we bought it**, with a maximum resolution of **TODO: add resolution** and a maximum frame rate of **TODO: add rate**. The camera is designed to provide the ability to collect images of the environment, as well as the ability to relay the information to the ground station in real-time. An image of the camera is shown in **TODO: add ref to fig**.

**TODO: figure of the camera chosen**

Finally, a on-board computer was integrated into the UAV, as it provides the ability to process the data collected by the sensors and cameras. The on-board computer chosen was the **TODO: add ref to where we bought it**, with a maximum processing power of **TODO: add power** and a maximum memory of **TODO: add memory**. The on-board computer is designed to provide the ability to process the data collected by the sensors and cameras, as well as the ability to relay the information to the ground station in real-time. An image of the on-board computer is shown in **TODO: add ref to fig**.

**TODO: figure of the on-board computer chosen**

## 14.2 Ground Station

The ground station is the control station that monitors the UAV in real-time. It is responsible for receiving telemetry data from the UAV and sending commands to update its flight plan. The ground station is also responsible for creating a geofence around the area of operation, monitoring the UAV's position and altitude in real-time, and tracking multiple UAVs simultaneously. The ground station is composed of the following components:

For the ground station, two main components are required: the ground control station and the backup control station. The ground control station is the main control station that monitors the UAV in real-time, receives telemetry data from the UAV, has the waypoint planning software, and sends commands to update the UAV's flight plan. The backup



control station is the secondary control station that serves as a backup in case the main control station fails. The backup control station has limited functionality, with the ability to receive telemetry data from the UAV and a manual override to take control of the UAV in case of an emergency.

The ground control station is composed of a computer, it can be a personal laptop or a desktop computer, with the waypoint planning software installed, in this case, the **TODO: add software** software as it can be seen in **TODO: ref**, and a communication modules to communicate with the UAV in real-time, which will be explained in Section 14.4. The backup control station is composed of a radio controller, which is a handheld device that allows the operator to take control of the UAV manually, and a communication module to receive telemetry data from the UAV in real-time. For the radio controller, the **TODO: add ref to where we bought them** was chosen, see **TODO: add figure**, as it provides a good balance between range, reliability, and ease of use as well as a good price-performance ratio.

**TODO: figure of the ground control station with the software**

**TODO: figure of the backup control station with the radio controller**

### 14.3 Reconnaissance Platform

The reconnaissance platform is the system that processes the data collected by the peripherals and the sensors on the UAV and provides insights to the end-user for the different reconnaissance tasks. The reconnaissance platform is responsible detecting and tracking objects, monitoring the environment, and generating alerts and notifications in case of critical events or failures. The reconnaissance platform is also responsible for coordinating the flight plans of the UAVs in a swarm, as well as designing the missions for the UAVs to perform specific tasks.

The components chosen for the reconnaissance platform were divided into two main components depending on where they run, the on-board reconnaissance platform and the off-board reconnaissance platform.

#### 14.3.1 On-Board Reconnaissance Platform

The on-board reconnaissance platform is the system that runs on the UAV and is responsible for processing the data collected by the UAV and providing insights to the end-user. The on-board reconnaissance platform is composed of a on-board computer and a communication module to communicate with the off-board reconnaissance platform.

For the on-board computer, multiple options were considered as represented in **TODO: add table reference**. The main use case for the reconnaissance platform is to process the data collected by the UAV in real-time and provide insights to the end-user. For this case, a computer with a high processing power, specially in the , is required as deep learning algorithms are used to detect and track objects in the environment. The on-board computer chosen for the reconnaissance platform was the **TODO: add ref to where we bought them** depicted in **TODO: add figure**, as it provides a good balance between processing power, reliability, and price-performance ratio. The reason to choose this on-board computer is that it provides the highest processing power commercially available. Having a stable and reliable on-board computer is crucial for the UAV design, as it allows for the UAV to process the data collected in real-time and provide insights to the end-user. Moreover, it

is widely used in the industry and has a large community of developers, which makes it easier to find support and documentation.

**TODO:** add table with the on-board computer options

**TODO:** add figure of the on-board computer

For the communication module, a 4G communication module was chosen, as it provides a high bandwidth required to send the data collected by the UAV in real-time to the off-board reconnaissance platform and a simple yet robust communication system. The communication module chosen for the on-board reconnaissance platform was the **TODO: add ref to where we bought them** depicted in **TODO: add figure**, as it provides a good balance between bandwidth, reliability, and price-performance ratio. For the use case of this project, a 4G communication module was enough as the environment where the UAV will operate has a good 4G coverage. On the other hand, if the UAV will operate in remote areas with limited infrastructure, a communication module would be more suitable.

**TODO:** add figure of the communication module

### 14.3.2 Off-Board Reconnaissance Platform

The off-board reconnaissance platform is the system that runs on a server and is responsible for coordinating the missions of the UAVs in a swarm, as well as generating reports and analyzing the data collected by the UAVs. The off-board reconnaissance platform is composed of a server, a database, and a communication module to communicate with the on-board reconnaissance platform.

For the server, multiple options were considered as represented in **TODO: add table reference**. The main use case for the reconnaissance platform is to process the data collected by the UAVs in real-time and provide insights to the end-user. For this case, a server with a stable and reliable connection is required. Moreover, the server should be able to be accessed remotely from anywhere in the world, as the end-user may be located in a different location than the server. For this the option that was chosen was the **TODO: add ref to where we bought them** as it provides the best price-ease of use ratio. The reason to choose a cloud provider is that it provides a stable and reliable connection, as well as the ability to be accessed remotely from anywhere in the world. Moreover, it is widely used in the industry and has a large community of developers, which makes it easier to find support and documentation.

**TODO:** add table with the server options

## 14.4 Communication System

The communication system is the system that allows the UAV to communicate with the ground station in real-time, as well as providing the connection to the reconnaissance platform. The communication system is responsible for sending telemetry data from the UAV to the ground station, receiving commands from the ground station to update the UAV's flight plan, and sending the data collected by the UAV to the reconnaissance platform for further analysis. Different communication systems can be used depending on the use case, such as 4G, 3G, , or , and the environment where the UAV will operate. The characteristics to consider when choosing a communication system can be seen in **TODO: add ref to the table in the requirements chapter**.

**TODO:** add table with the communication system options

For this project, two communication systems were chosen the on-board communication system and the off-board communication system.

#### 14.4.1 On-Board Communication System

The on-board communication system is the system that connects the UAV with the ground station in real-time. The on-board communication system is composed of a communication module that sends telemetry data from the UAV to the ground station and receives commands from the ground station to update the UAV's flight plan. The on-board communication system is responsible for providing a stable and reliable connection between the UAV and the ground station, as well as a high bandwidth to send the data collected by the UAV to the reconnaissance platform. The main requirements for the on-board communication system are a high reliability, a low latency, and long range.

For this case, a communication module was chosen, as it satisfies the requirements for the on-board communication system as well as not needing a cellular network to operate, thus making it more versatile and ideal to operate in remote areas. The communication module chosen for the on-board communication system was the **TODO: add ref to where we bought them** depicted in **TODO: add figure**, as it provides a good balance between reliability, latency, and range. The reason to choose a communication module is that it provides a stable and reliable connection, as well as a low latency and long range. Moreover, it is the defacto standard for UAV communication systems, as it provides a good price-performance ratio.

**TODO:** add figure of the communication module

#### 14.4.2 Off-Board Communication System

The off-board communication system is the system that connects the on-board reconnaissance platform with the off-board reconnaissance platform. The off-board communication system is composed of a communication module that sends the data collected by the UAV to the off-board reconnaissance platform for further analysis. The off-board communication system is responsible for providing a stable and reliable connection between the on-board reconnaissance platform and the off-board reconnaissance platform, as well as a high bandwidth to send the data collected by the UAV in real-time. The main requirements for the off-board communication system are a high bandwidth, a secure connection, and the ability to receive data from multiple UAVs simultaneously.

For this case, a 4G communication module was chosen, as it satisfies the requirements for the off-board communication system as well as providing a high bandwidth to send the data collected by the UAV in real-time. The 4G communication module chosen for the off-board communication system was the **TODO: add ref to where we bought them** depicted in **TODO: add figure**, as it provides a good balance between bandwidth, reliability, and price-performance ratio. A 4G communication module was chosen as the environment where the UAV will operate has a good 4G coverage. On the other hand, if the UAV will operate in remote areas with limited infrastructure, a communication module would be more suitable.

**TODO:** add figure of the communication module

## 15. IMPLEMENTATION

**TODO:** write this chapter

## 16. TESTING

**TODO:** write this chapter



# **Part V**

## **Results**





# **Part VI**

## **Conclusions**

## 17. CONCLUSIONS

**TODO:** write this chapter

## 18. FUTURE WORKS

**TODO:** write this chapter

## 19. SOCIO-ECONOMIC ENVIRONMENT

**TODO:** write this chapter



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