Fighting Wildfire with Unmanned Aerial Vehicle

Summary

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key words : 关键词 1; 关键词 2; 关键词 3

Budget Request

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To: The group of Governors
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Sincerely yours,
MCM Team 2120710

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1   Introduction

1.1   Restatement of the Problem

Many people...Therefore we are facing the following problems:

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- aaaaaaa

1.2   Our Works

- aaaaaaa

- aaaaaa

2   Assumptions and Notations

2.1   Assumptions

Due to the lack of necessary data, we make the following assumptions to help us perform modeling:

1. The circumstance remain unchanged in the time interval we investigated.

2. We omit the possibility of any other kinds of aerial vehcle or flying creature hitting our UAV.

3. Accroding to Bureau of Meteorology of Australian Government, litghting is the major causation of bushfire in some area, Victoria included. [1] Based on this fact, we evaluat the possibility for a certain place to catch fire with the possibility of a lightning to occour there.

4. We adopt the Equal Possibility Hypothesis when our UAVs are patrolling for the purpose of monitoring any outbreak of fire.Under this hypothesis, an area of high possibility to catch fire indicates

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the frequency of fire outbreak here is high, thus the command center should pay closer attention to this area to alarm fire outbreaks timely.

5. All UAVs are equipped with a timer.

6. All UAVs are directed by a preprogrammed system given by us, which means they are all automatic.

7. Staffes are always available in any charging stations, which guarantees the UAVs will always work in the stanterd situation.

8. A drone can carry either a set of thermal imaging cameras and telemetry sensors or a radio repeater. The former combination can and can only detect any fire outbreak, while the latter can and can only extend the valid zone of radio wave signals.

2.2 Notations

2.2.1 *ijk*-coordinate system

Before illustrating the notations for model construction, we would like to introduce a special coordinate system called ***ijk*-coordinate system**[2], which was first proposed by Uber Technologies Inc. Discrete hexagon planar grid systems naturally have 3 coordinate axes spaced $120°$ apart. We refer to such a system as an *ijk* coordinate system, for the three coordinate axes i, j, and k.

2.2.2 Notations

Here are all the notations and their meanings in this paper.

3 Model Construction

blablablabla

4 Conclusion

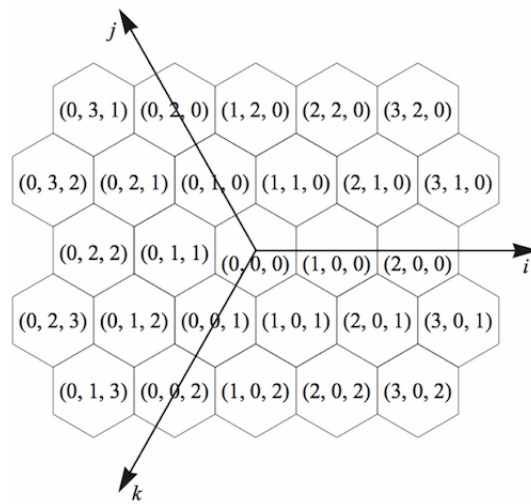We build a.....interesting findings:
- aaaaaaa

Figure 1: One possible map example that using the *ijk* coordinate system

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References

[1] M. Kilinc and J. Beringer, "The spatial and temporal distribution of lightning strikes and their relationship with vegetation type, elevation, and fire scars in the northern territory," *Journal of Climate*, vol. 20, no. 7, pp. 1161 – 1173, 01 Apr. 2007. [Online]. Available: https://journals.ametsoc.org/view/journals/clim/20/7/jcli4039.1.xml

[2] "The h3 core library documentation: Coordinate systems," https://h3geo.org/docs/core-library/coordsystems.

Appendices

Here is Code we used in our model, which python is the main development language.

Appendices A

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Table 1: Notations used in model construction

Notation	Meaning
$M(i,t)$	Location of the i-th drone I at time t
$R(j,t)$	Location of the j-th drone II at time t
$h(x,y,z)$	Elevation of the point (x,y,z)
$S(x,y,z)$	Fire history of the point (x,y,z) in the passed 5 years
$a_i(x,y,z)$	Fire history of the point (x,y,z) in the $2020-i$-th year, $i \in [1,5] \cap \mathbb{N}$
$F(x,y,z)$	Vegetative and structural condition of the point(x,y,z)
$S(i,x,y,z,t)$	Strength of the signal from the i-th drone at point (x,y,z) at time t
$E(x,y,z,N)$	Supervisory density of the point (x,y,z) when there are N drones in the field
$Slope(x,y,z)$	Maximum slope of the point (x,y,z)
γ	Factor used to calculate the weight of slope in causing bushfire
$\beta(x,y,z)$	Weight of slope in causing bushfire
$\omega(x,y,z)$	Decreasing rate of signal at point (x,y,z)
α	Elevational factor
$Chg(q,x,y,z)$	Location of the q-th charging station
V_{max}	Maximum flying velocity of a drone
N_{SSA}	Amount of drone I
N/rep	Amount of drones II
PF	Power consumption for a flying drone
PH	Power consumption for a hovering drone
$t_{fl}(t,l)$	Flight time of the l-th drone until time t
$t_{hov}(t,l)$	Hovering time of the l-th drone until time t
T	Duration of a day (i.e. $1440 \, \text{min}$)
t	Current time
Br	Total battery power of a drone
Ini	Location of the EOC