Project Charter: FlyNet

Autonomous Multi-rotor Mapping and Localization  
Sponsored by: United Technologies Research Center

|  |  |  |  |
| --- | --- | --- | --- |
| Project Title: | FlyNet | | |
| Brief Project Description: | Design a team of autonomous robots consisting of multi-rotors and ground robots to map and localize in an unknown environment, while searching for known targets. | | |
| Project Manager: | Drew Ellison | | |
| Signature: |  | Date: |  |
| Machine Shop: | Matt Rhode | | |
| Signature: |  | Date: |  |
| Instrumentation Shop: | Trudy Schwartz | | |
| Signature: |  | Date: |  |
| Faculty Adviser: | Eric Frew | | |
| Signature: |  | Date: |  |
| Course Coordinator: | Joe Tanner | | |
| Signature: |  | Date: |  |

Team Organization Chart

Roles and Responsibilities

|  |  |
| --- | --- |
| **Members** | **Role/Description** |
| **United Technologies Research Center**  **(Zohaib Mian)** | **Project Sponsor:** Will provide funding and academic support in technical areas in which the team lacks experience. Will confirm that the solution the team designs is to the specifications that UTRC requires |
| **Professor Eric Frew** | **Project Advisor:** Faculty advisor for your project. |
| **Drew Ellison** | **Project Manager**: In charge of managing team directive, project scope, and directly communicating with the customer regularly. |
| **Austin Anderson** | **Systems Engineer:** Technical leader of the team. Works closely with the project manager to establish team goals, deadlines, and make large technical decisions. |
| **Steve McGuire**  Tyler Clayton  Taylor Dean | **Computer Vision Team:** Responsible for developing and integrating computer vision algorithms for mapping and localizing in a 3-D, obstacle filled environment. |
| **Ed Meletyan** | **Simulation Team:** Responsible for working with the computer vision and controls teams in order to develop robust MATLAB simulations of the estimation and control algorithms for proof of concept, rapid development and testing of flight software. |
| **Bryce Hill**  Prashant Ganesh  Matt Busby | **Controls Team:** Responsible for developing robust control algorithms for a multi-rotor vehicle in order to produce reliable, autonomous indoor flight |

Scope & Objectives

The FlyNet team seeks to design and test a team of multi-rotor drones armed with onboard computers and sensor suites that will autonomously map an unknown building with no prior information in a GPS denied environment. This goal requires the development and integration of real time, online autonomous controllers, state estimators, and 3D dense point cloud map generation software.

The Flight Controls team will interface an onboard computer with the multi-rotor Pixhawk autopilot in order to pull sensor information and to send attitude commands. The team will design a position controller based on obstacle avoidance and pattern/building searching techniques that will generate real time attitude commands. These attitude commands will be sent to the autopilot, which will then be ran by the onboard autopilot controllers. Once these controllers have been developed, the team will test the algorithms using a human-in-the-loop position reference command in order to test the efficiency of the controllers and tune any appropriate parameters.

In parallel with controller development, a vehicle state estimator will be developed in order to estimate vehicle velocity, attitude, and position. This estimator will pull sensor information from the Pixhawk autopilot and run Kalman filtering techniques in order to provide these state estimates. Once developed and integrated, these estimators will be tested by manually flying the vehicle in a VICON space, which provides a ground truth measurement of the multi-rotor state. The estimator performance will then be evaluated by comparison with these ground truth measurements.

The Computer Vision Team will develop and test an algorithm to perform simultaneous localization and mapping (SLAM). The end goal of this team is to run this algorithm on the multi-rotor platform. However, to simplify the development process, the team will prototype these algorithms on a ground robot with a human controller. This mitigates the risk of breaking onboard processors and sensors by removing the flight aspect of testing. Additionally, using a ground robot should simplify the initial development of the algorithm, since ground robots do not have the fast, complicated dynamics of an aerial vehicle.

After the development of these individual aspects, the SLAM team will integrate their algorithm on the aerial platform. The deliverable for this semester is then a single multi-rotor that can autonomously map an unknown territory. Once this ability has been established, the team will pursue adding target searching and tracking capabilities.

Basic Schedule Overview

* 8/25/15 – 9/29/15 – Initial Design Phase
  + Fly existing aerial vehicles manually (8/25/15 – 9/15/15)
  + Interface onboard computer with autopilot (8/25/15 – 9/22/15)
  + Design indoor flight controller architecture (8/25/15 – 9/22/15)
  + Design aerial vehicle state estimation algorithm (8/25/15 – 9/22/15)
  + Investigate existing software packages for aerial vehicle simultaneous localization and mapping (8/25/15 – 9/15/15)
  + Decide on system hardware (onboard computers, cameras, sensors, etc.) (8/25/15 – 9/22/15)
* 9/29/15 – 10/21/15 – Development and Test Phase (Preparation for Flight/Algorithm Qualification Testing)
  + Integrate flight controller and test on vehicle (9/22/15 – 10/13/15)
  + Integrate state estimator on vehicle (9/22/15 – 10/13/15)
  + Official controller FQT due (10/21/15)
  + Official estimator FQT due (10/21/15)
  + Integrate/prototype SLAM algorithm on ground robot using only aerial vehicle sensors (9/29/15 – 10/21/15)
  + Official SLAM AQT due (10/21/15)
* 10/21/15 – Mid-Semester Presentation
* 10/21/15 – 11/17/15 – Delta FQT/AQT
  + Integrate revisions/code fixes found during AQT/FQT
* 11/17/15 – 12/12/15 – SLAM-Flight Integration Phase
* 12/13/15 – Final Presentation
* 1/15/16 – 5/15/16 – Development of target ID and tracking, more robust flight control in mapped enviroments

Resource List

|  |  |  |
| --- | --- | --- |
| **Resource** | **Point of Contact** | **Reason for Need** |
| Aerospace Machine Shop | Matt Rhode | Safety concerns for indoor flight testing |
| Aerospace Instrumentation Shop | Trudy Schwartz | Electronics equipment |
| MATLAB | OIT | To create simulations and prototypes of flight software |
| Previous year’s knowledge base | Drew Ellison | Will be used to aid in the decisions of hardware choices and designs of controllers and estimators. |

Budget Information

|  |  |  |
| --- | --- | --- |
| **Source/Expense Item** | **Project Funds Available** | **Expected Expenses** |
| UTRC | $10,000 |  |
| Previous Expenditures |  | $8,000 |
| Forecast Expenditures |  |  |
| New quad-rotor platform |  | $3,000 |
| Onboard Computers |  | $630 |
| Sensors/Cameras |  | $3000 |
| Vehicle materials |  | $500 |
| Subtotal | $10,000.00 | $7,130.00 |
| Estimated Final Balance | $2,870.00 |  |

Communication Plan

Include anything pertinent to communication. This can include how often you will meet, where information is stored, and who must be contacted for certain tasks. For example, you might want to include who must be contacted and when in order to complete a purchase order.

The FlyNet graduate team will regularly meet twice a week in the Fleming laboratory:

* Tuesday : 3:00PM – 4:50PM
* Wednesday: 11:00AM – 12:50PM

All documentation and software will be kept on the team GitHub at the following address:

* [www.github.com/dme722/FlyNet](http://www.github.com/dme722/FlyNet)

In order to perform purchase orders, please contact Drew Ellison ([dme722@gmail.com](mailto:dme722@gmail.com)) or Austin Anderson ([Austin.m.anderson@colorado.edu](mailto:Austin.m.anderson@colorado.edu)).

Change Log