

Tez Outline

1 - Introduction

2 – Marine Vessels Model

- Kinematic Model

- Dynamic Model

- Thrusters Allocation

3- Line of Sight Method

- curved line of sight

- time-varying lookahead distance guidance

4- Path Generation Algorithm

- curved path generation

- speed and acceleration references generation

5- Model predictive control

- intro. MPC

- MPC model of ship dynamic

(DİNAMİK ENGELLERİN OLDUĞU ORTAMDA COLREG KURALLARINA GÖRE WAYPOINT TAKIBİ YAPMAYI BAŞARIRSAM COLREG DURUMLARINI VE MPC İLE MODELİNİ ANLATAN BİR BÖLÜM EKLEMİYİ DÜŞÜNÜYORUM)

6- Simulations (akıntılı, akın olmadan, statik engellerin olduğu ortam)

7- conclusions