UAV Route Planning Strategies for Efficient Coverage Search in Complex Environments

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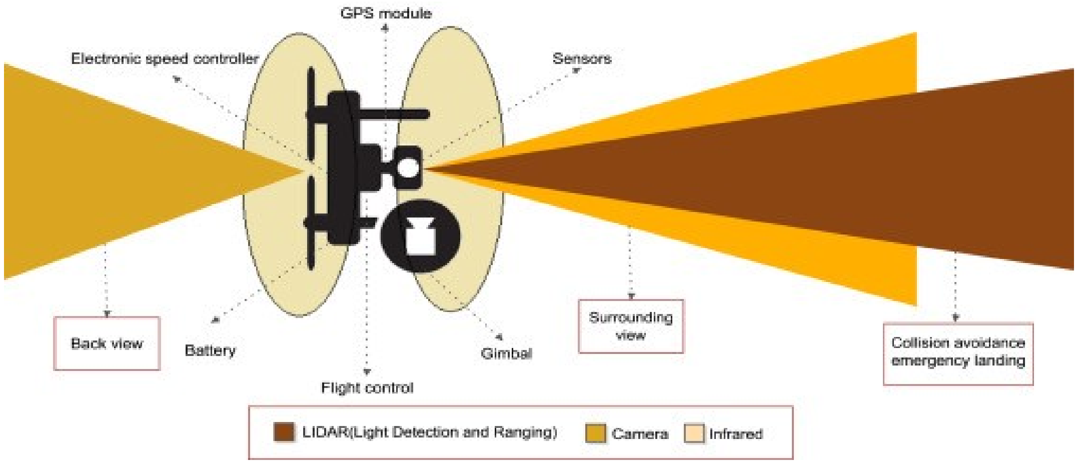
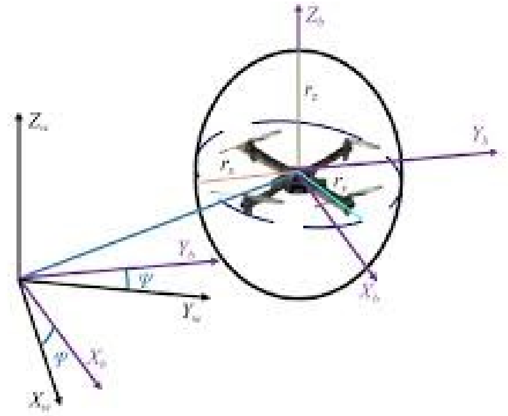
UAV Route Planning





Reference: https://www.sciencedirect.com/science/article/pii/S0140366419308539

Overview of approaches

- Classical algorithms
- Probabilistic methods
- Nature-inspired algorithms
- Multi-UAV coordination
- Environment-specific approaches
- Military applications

Classical approaches

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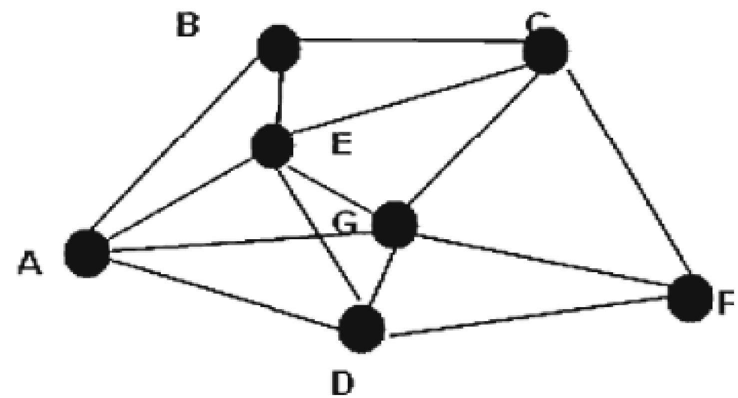
- Dijkstra's Algorithm
- A* Algorithm
- Bellman-Ford Algorithm
- Floyd-Warshall Algorithm



$$A[i][j] = \begin{pmatrix} 0 & 1 & 0 & 1 & 1 & 0 & 0 \\ 1 & 0 & 1 & 0 & 1 & 0 & 1 \\ 0 & 1 & 0 & 0 & 0 & 1 & 1 \\ 1 & 0 & 0 & 0 & 1 & 1 & 1 \\ 1 & 1 & 0 & 1 & 0 & 0 & 1 \\ 0 & 0 & 1 & 1 & 0 & 0 & 1 \\ 0 & 1 & 1 & 1 & 1 & 1 & 0 \end{pmatrix}$$

Reference: Multiple UAVs path planning algorithms: a comparative study (Paper 1)

Classical approaches

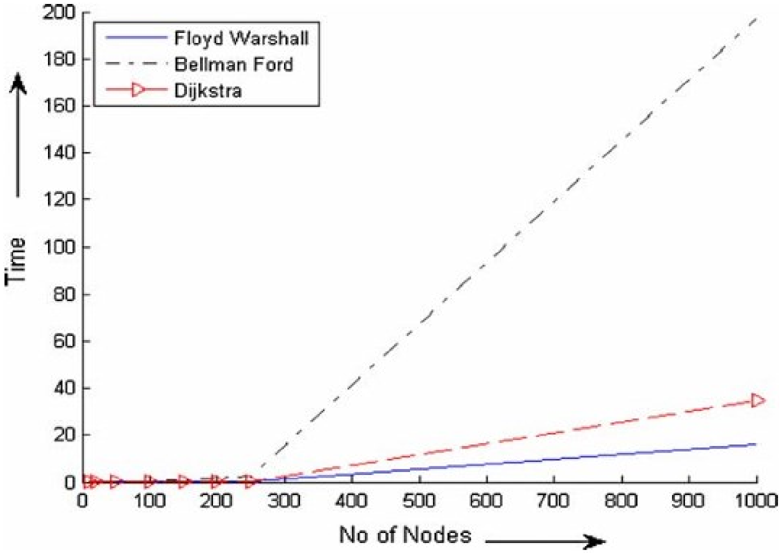


Fig. 5 Computation efficiency of search algorithms

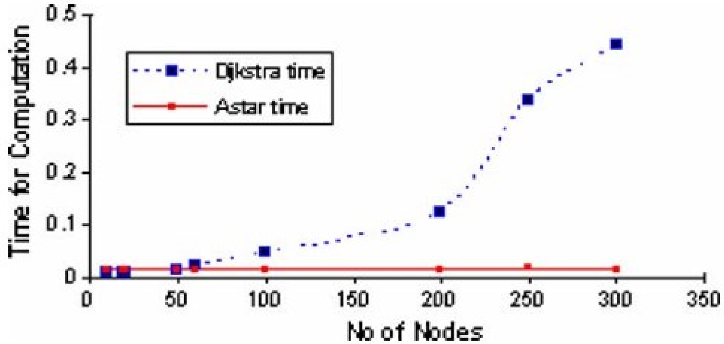
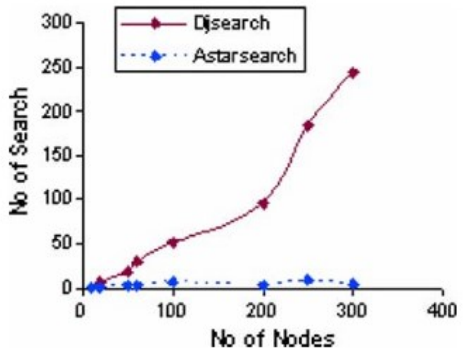


Fig. 6 Astar versus Dijkstra search

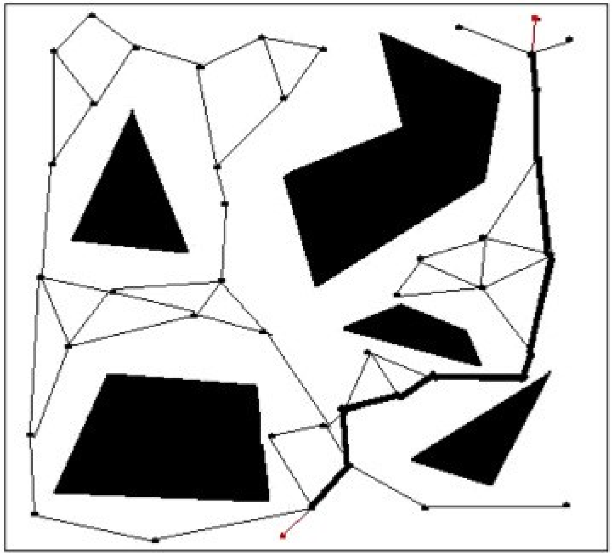
Fig. 7 Dijkstra versus astar



Reference: [Multiple UAVs path planning algorithms: a comparative study](#) (Paper 1)

Probabilistic methods

- **Probabilistic Roadmap Method (PRM)**
  - Efficient for high-dimensional configuration spaces
  - Two phases: learning phase and query phase
  - Handles complex 3D environments effectively
- **Key features**
  - Random sampling of configuration space
  - Creation of roadmap for path planning
  - Efficient for large/complex environments



Reference: https://www.sciencedirect.com/science/article/pii/S0140366419308539

Probabilistic methods

- **Enhancements for UAV Applications**
  - Octree-based environment representation
  - Safety-aware sampling
  - Bounding box array for focused sampling
  - Connectivity evaluation for feasible paths

- **Advantages**
  - Handling obstacle avoidance well
  - Computationally efficient for large environments
  - Adaptable to different types of environments

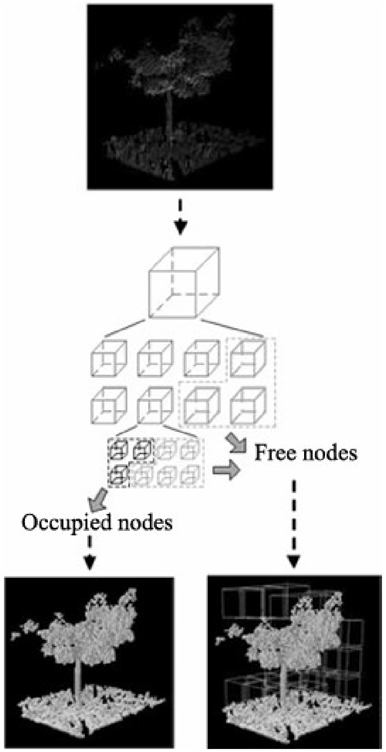


Fig. 1 The occupied voxels and free voxels are extracted from 3D data during octree building

Reference: Path Planning in Complex 3D Environments Using a Probabilistic Roadmap Method – (Paper 2)

Nature-inspired algorithms

- **Grey Wolf Optimization (GWO)**
  - Inspired by social hierarchy and hunting behavior or grey wolves
  - Balances exploration and exploitation effectively
- **Particle Swarm Optimization (PSO)**
  - Efficient for continuous optimization problems
  - Well-suited for dynamic UAV path plannig
  - Based on social behavior of bird flocking/fish schooling
- **Ant Colony Optimization (ACO)**
  - Effective for discrete optimization and adaptive path planning
  - Mimics foraging behavior of ant colonies

Nature-inspired algorithms

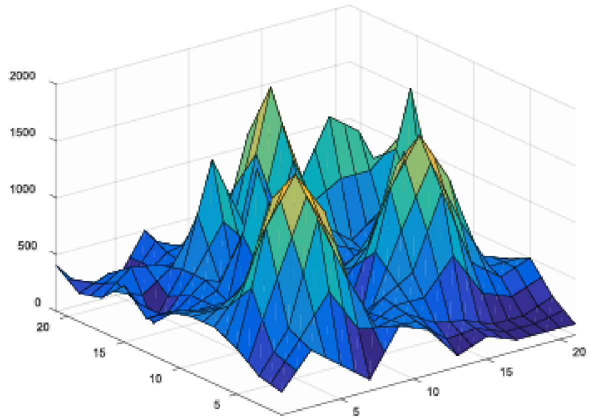


FIGURE 1. Environmental model for three-dimensional planning.

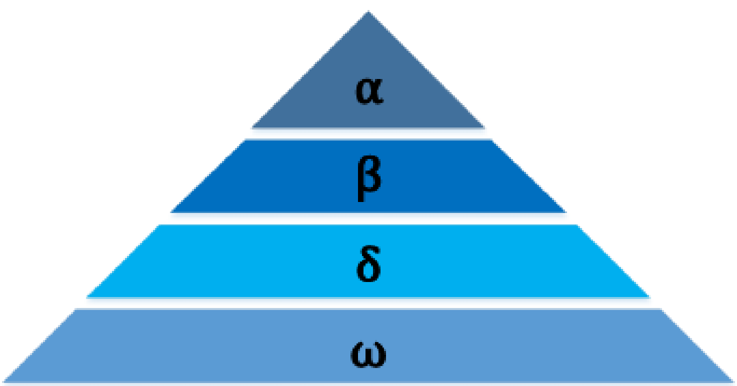


FIGURE 4. The social hierarchy of the grey wolf.

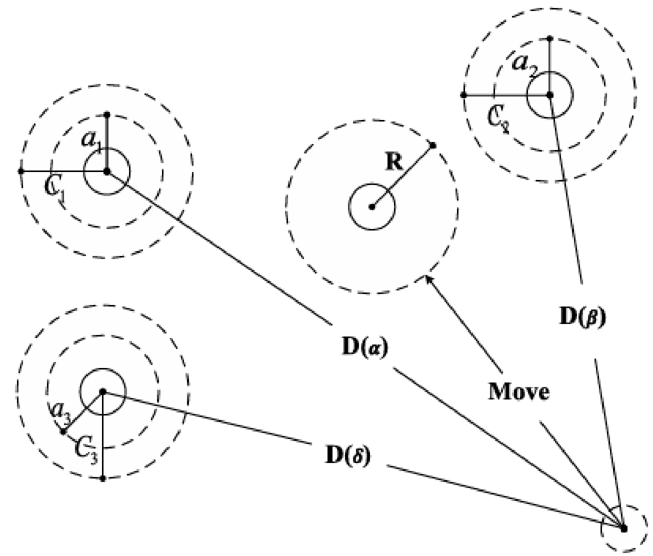


FIGURE 5. Grey wolf population location update process.

Reference: Path Planning of UAV Based on Improved Adaptive Grey Wolf Optimization Algorithm – (Paper 4)

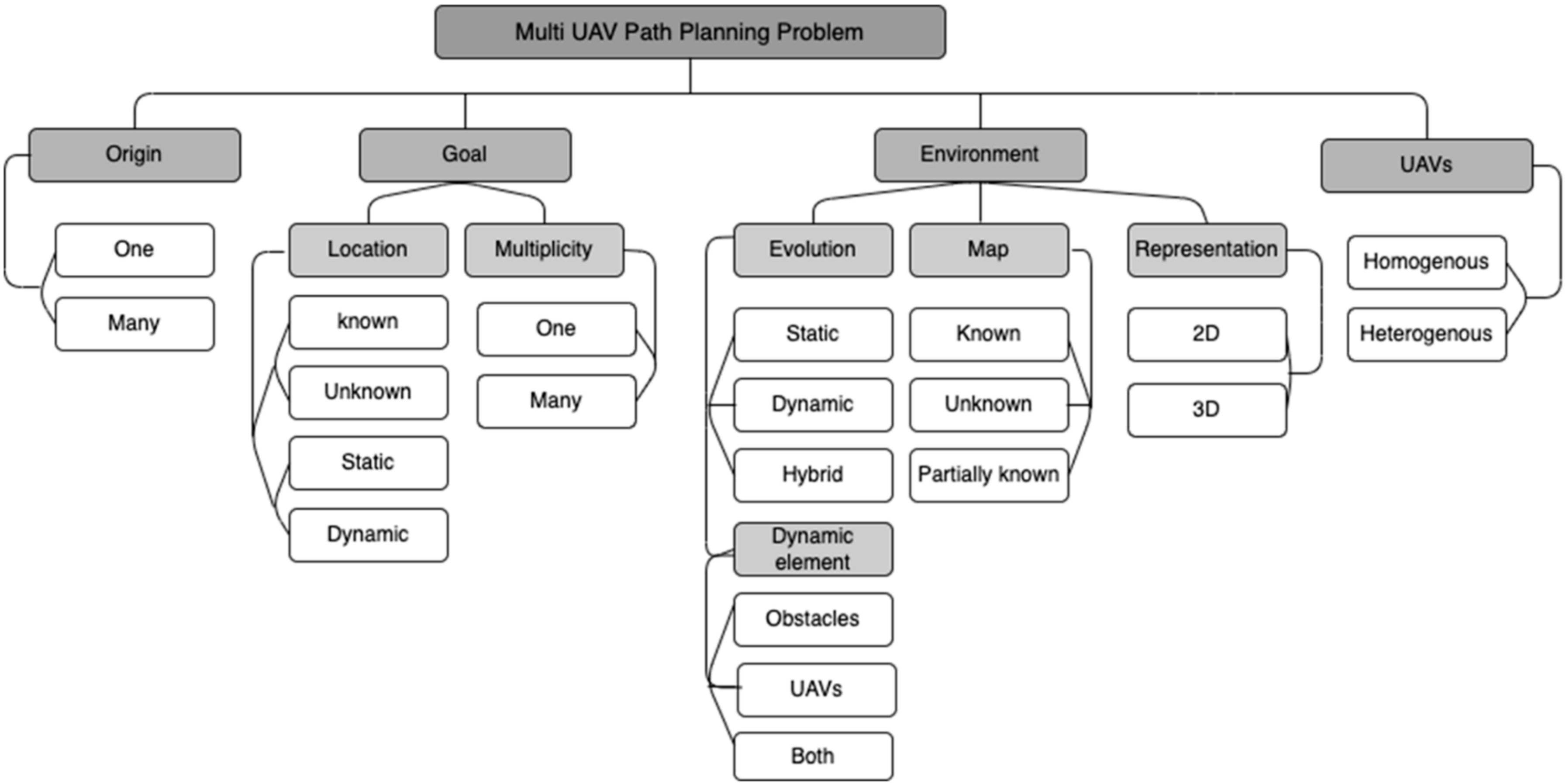
Multi-UAV coordination

- **Extended from single-agent to multi-agent planning**
  - Multiple Traveling Salesman Problem (MTSP)
  - Vehicle Routing Problem (VRP)

- **Key challenges**
  - Grouping and task allocation among UAVs
  - Multi-objective optimization (e.g. distance, energy, risk)
  - Dynamic environments (e.g., synchronization precedence)

- **Solution methods**
  - Meta-heuristic algorithms
  - Neural Networks (NN) for complex pattern learning
  - Hybrid approaches combining multiple algorithms

Multi-UAV coordination



Reference: https://www.mdpi.com/2227-7390/11/10/2356

Environment-specific approaches

- **Focus**
  - River search scenarios (Yao et al.)

- **Key components**
  - Gaussian Mixture Model (GMM) for probability distribution
    - Identifies high-value river segments and adjusts greedily
  - Approximation Insertion (AI) method for prioritization
    - Constructs search route iteratively

- **Innovative aspects**
  - Uses prior information to estimate target locations
  - Adapts to river geometry and probability distributions
  - Balances detection probability and travel time

Environment-specific approaches

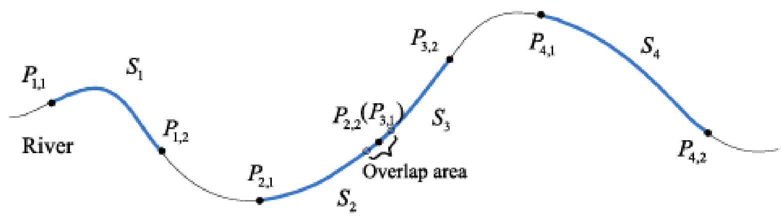


Fig. 2. Illustration of extracted river subregions.

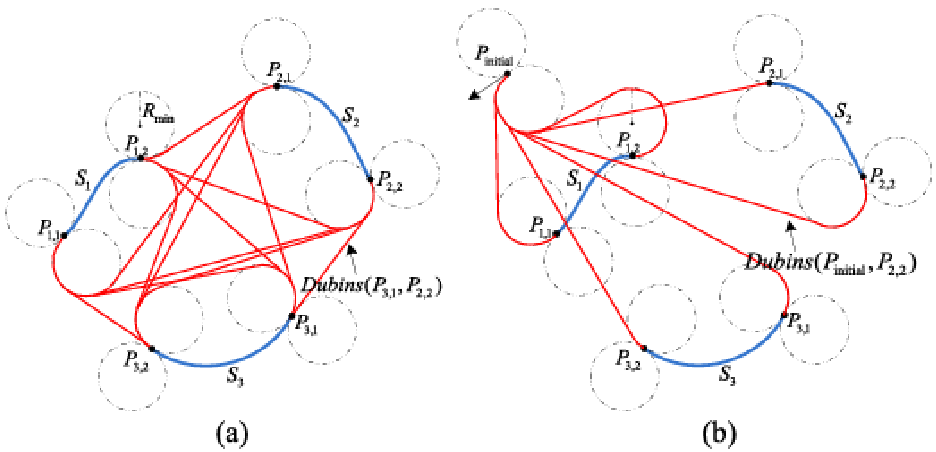


Fig. 3. Illustration of synthesized graph using Dubins connections. (a) Connecting nodes. (b) Connecting UAV initial point and nodes.

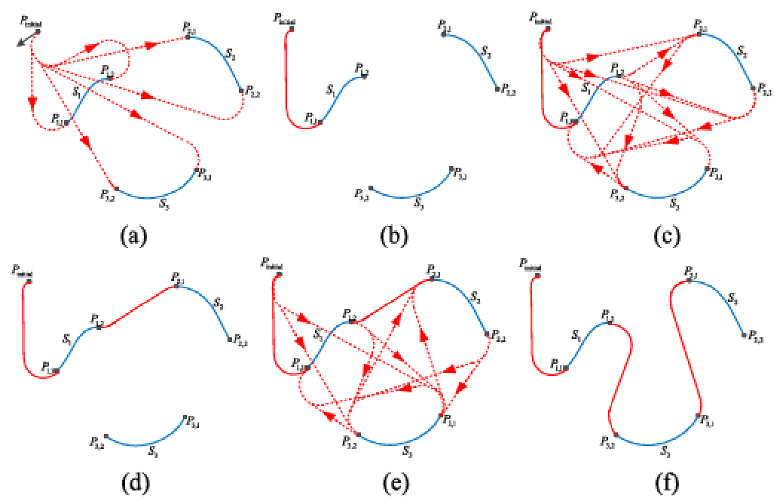


Fig. 4. Illustration of AI method. (a) Find the best edge. (b) First time (choose S_1). (c) Find the best edge. (d) Second time (S_2 is stacked after S_1). (e) Find the best edge. (f) Third time (S_3 is inserted between S_1 and S_2).

Reference: Optimal UAV Route Planning for Coverage Search of Stationary Target in River – (Paper 5)

Military applications

- aa

Comparison of approaches

- aa

Future challenges and research directions

- aa

Conclusions

- aa