Utility Based Scheduling for Multi-UAV Search System in Disaster Scenarios

Kosei MIYANO, Ryoichi SHINKUMA, Eiji OKI, and Takehiro SATO

***Abstract*—Micro or small unmanned aerial vehicles (UAVs) is a promising solution for finding people who have disappeared because of getting lost in unexpected situation like disaster. It takes long time to analyze the acquired image data for the target recognition due to the limited computational resource of small UAVs. In addition, the data transfer time can increase in the disaster-hit areas due to the damage of communication infrastructures. However, the prior researches did not consider both processing time of the acquired data and data transfer time, despite the temporal requirement in the surveillance scenarios. Therefore, this paper proposes a scheduling method of multi-UAV search system that considers processing time of image data and data transfer time. We present the utility-based problem formulation that ensures the freshness of individual obtained piece of information while obtaining as many pieces of information as possible for a certain period. Simulation results verify that the proposed scheduling method ensures the freshness of individual obtained piece of information while delivering as many pieces of information as possible for a certain period by evaluating each information in terms of two metrics: i) elapsed time from start time and ii) elapsed time after acquired.**

***Index Terms*—uav (unmanned aerial vehicle), target search, scheduling, edge computing**

I. INTRODUCTION

The number of deaths and missing people due to natural disasters is still a serious problem in many countries. According to a report by Centre for Research on the Epidemiology of Disasters [1], the average number of deaths and missing people due to natural disasters occurred all over the world, such as earthquakes, hurricanes, forest fires, and floods, from 2006 to 2015 was approximately 70,000. In order to reduce the number, one of the solutions to reduce the number is to increase the number of rescue teams. The report by Japan Ministry of Defense after the great east Japan earthquake suggests that it is necessary to secure manpower through guidelines for the concentration of units in the immediate aftermath of a disaster. However, a huge budget is required to secure manpower and the risk of secondary damages in disaster occurrence areas is serious remaining issues to be solved [2].

Micro or small unmanned aerial vehicles (UAVs), also known as drones, are expected to be emerging solutions to solve the above problem in areas where humans and ground vehicles cannot easily step into like disaster-damaged areas. Technological advances in the recent years have led to the emergence of smaller and cheaper UAVs, which have some functions such as transporting relief supplies, collecting data by using equipped sensors and operating as adhoc wireless mesh network infrastructure in such isolated areas [3]–[5]. Collecting image data is especially important because it is applicable to many use cases such as search and rescue mission, fire detection and surveilance. Since there are time constraints in such situations, UAVs need to collect sensor data as soon as possible. In the great east Japan earthquake, as time passed, the number of deaths and missing people dramatically increased [6].

Surveillance using multiple UAVs has been receiving increasing attention for reasons such as increase in system reliability, robustness, and efficiency [7]–[11]. However, despite the temporal requirement in these surveillance systems, it is assumed that the user can obtain necessary information as soon as UAV acquires image data: both processing time of image data and data transfer time are not taken into consideration. In the practical situation, it takes long time to analyze images for target recognition due to the limited computational resource of small UAVs. In addition, the data transfer time can increase in the disaster-hit areas due to the damage of communication infrastructures.

Therefore, this paper proposes a scheduling method of multi-UAV search system that considers processing time of image data and data transfer time. We present the problem formulation of the proposed scheduling method that maximizes the user's utility, which is calculated from the efficiency of obtaining results from analyzed data and the interval of obtaining the results. We show the results of performance evaluation to verify that the proposed method ensures the freshness of individual obtained piece of information while delivering as many pieces of information as possible for a certain period.

The remainder of this paper is organized as follows. Section II discusses the related work. Section III presents the system overview and proposed scheduling method. Section IV then provides the performance evaluation of the proposed method through a simulation, followed by the extension to two-dimensional model in Section V. Finally, Section VI concludes this paper.

II. RELATED WORK

This section discusses the prior works related to this paper. First we will discuss UAV Applications in disaster areas. Among the application scenarios that will be introduced in Section II-A, data collection using equipped sensors is carried out in our system. Next the prior researches on Multi-UAV

K. Miyano, R. Shinkuma, E. OKI, and T. SATO are with Graduate School of Informatics,Kyoto University,Yoshidahon-machi, Sakyo-ku, Kyoto-shi, Kyoto, Japan, 606-8501. e-mail: (kmiyano@icn.cce.i.kyoto-u.ac.jp, {shinkuma, oki, takehiro.sato}@i.kyoto-u.ac.jp)

cooperation for area coverage is discussed since it is also assumed in our search system as mentioned in Section I. Finally, we also discuss prior works on inter UAV cooperation for computing and computing on UAVs with edge computing. In our system, it is assumed that the collected data is processed locally onboard UAVs with edge computing but inter UAV cooperation for computing is not considered since the overhead of transmission between UAVs is large and is out of the scope of this paper.

A. UAV Applications in disaster areas

Transporting relief supplies by UAVs is very important since there is a possibility that humans and ground vehicles cannot easily step into the disaster areas. Bamburry mentioned the ability of a UAV to deliver medical products to remote and hard-to-reach areas [12]. For example, in the devastating 2010 earthquake in Haiti, a UAV delivery system was used to deliver medicine to camps set up after the disaster [13].

UAVs can also collect data by using equipped sensors. In [14], Each UAV is provided with a mobile optical sensors and image transmission modules developed by the Wada et al. The optical sensor which is a combination of a IR sensor and a visible-light sensor enables data collection even at night or against smoke in the disaster areas. After the launch, a UAV executes auto flight along the way points by recognizing its positions and obtains the necessary video/image information. The UAV transmits it to the server and shares it with users via the Internet.

UAVs also often operate as adhoc wireless mesh network infrastructure, which is called Flying Ad Hoc Networks (FANET) [15]. In 2016, Sánchez et al. aim to provide connectivity for rescuers and disaster victims using UAVs [16]. They propose a Jaccard-based movement rules to define the UAVs best positions for providing the best communication service to the victims in a urban disaster scenario. Finally they compare among several local search computational intelligence algorithms implemented such as simulated annealing, hill climbing, and random walk for deciding the best tactical UAV movements.

B. Multi-UAV cooperation for area coverage

Maza et al. provided a pioneer work in cooperatively searching a given area to detect objects of interest by UAVs [8]. First they determine relative capabilities of each UAV, based on factors like flight speed, altitude required for the mission, sensitivity to wind conditions and sensing width. Then, they divide the whole area by divide-and-conquer, taking into account the UAV ’ s relative capabilities and initial locations. Finally, they set the waypoints of each UAV so that the number of turns needed along a zigzag pattern is minimized.

Zhao et al. in 2016 tackled the challenging problem of not only searching the target area for a lost target but also tracking the target [10]. In the tracking stage, each UAV keeps desired distance with the target, coordinating the angular separation between neighboring UAVs to the same angle. if there is a shelter between UAV and target, the target state is predicted by the target model with the former target information. In the searching stage, multi-UAVs divide the search region equally which is determined by the target lost duration time and speed and then search for the target by the method of shrinking annulus. The switch tactics between the tracking stage and the searching stage was also proposed.

In 2017, Hayat et al. proposed a multi-objective optimization algorithm to search and plan paths for UAVs [17]. UAVs search for the target cooperatively and soon after some UAV detects the target, the other UAVs takes positions for relay chain formation between the UAV and a base station. The algorithm aims to minimize the mission completion time, which includes the time to find the target and the time to setup a communication path. Finally they compare among three strategies that perform search by UAVs in a similar manner but have a different path planning in terms of the mission completion time.

C. Multi-UAV cooperation for computing

UAV Applications in disaster areas require UAVs to deal with intensive computation tasks such as image/video processing, pattern recognition and feature extraction. Computation offloading is very important since computational power of a single UAV is limited.

1) inter UAV cooperation: Ouahouah et al. in 2017 proposed the use of offloading mechanism among UAVs equipped with IoT devices [18]. Each IoT task is partitioned into a set of sub-tasks that can be executed simultaneously among a cluster of UAVs. The sub-tasks is assigned to UAVs based on their power supply, resources in terms of memory and CPU computation, and their on-board IoT devices. Two solutions were proposed for computation offloading:Energy aware optimal task offloading and Delay aware optimal task offloading. The former maximizes the UAVs lifetime by electing the UAVs with higher power supply. The latter reduces the response time by favoring the selection of UAVs with more resource capacities.

In 2018, Valentino et al. proposed an opportunistic and adaptive computational offloading scheme between UAV clusters [19]. A cluster head will broadcast a ‘ hello ’ message indicating their presence and available resources and then a local cluster send an offloading request to a desired cluster head. a local cluster decides if it is better to do the task alone or to offload, estimating response time for doing the computational offloading and processing the given task through computing power, size of task, bandwidth, and data rate of wireless network.

2) Edge computing: Edge computing has been proposed as an effective mean of supplementing computational resources for UAVs [20], [21].

Motlagh et al. in 2017 demonstrated how UAVs can be used for crowd surveillance based on face recognition. Due to the computational overhead required by such a use case and given the limited power supply of UAVs, they performed the offloading of video data processing to a mobile edge computing node. The obtained results showed clearly the benefits of computation offloading compared to the local processing of video data onboard UAVs in saving energy and quickly detecting and recognizing suspicious persons in a crowd.

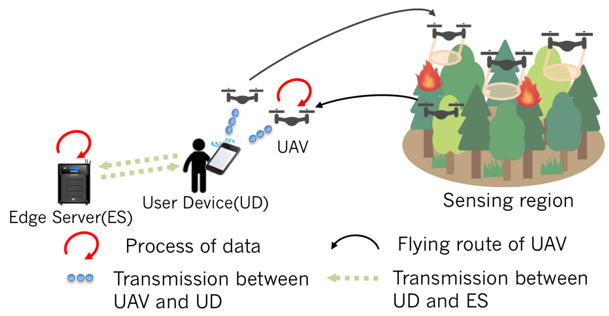

Fig. 1. System illustration

Messous et al. in 2017 tackled a computation offloading problem with three different devices:UAV, base station and edge server, which carry out the heavy computation tasks. They prove the existence of a Nash Equilibrium and design an offloading algorithm that converges to the optimal point. Their cost function was defined as a combination of two performance metrics: energy and delay. They finally achieved better value of the utility using the the offloading algorithm, compared to computing on: edge server, base station and drone respectively.

III. Proposed method

A. System overview

1) System model: Figure 1 depicts the system model we assume in this paper. The system consists of a user device (UD), multiple UAVs, and an edge server (ES), the roles of which are described as below. The UD is the central operating entity in the system and operates all the UAVs and the ES; the UD determines flying routes and timings of UAVs and assigns workloads of computing sensor data to UAVs and the ES. The UD also works to forward sensor data received from UAVs to the ES and to obtain computational results from both UAVs and the ES.

Each UAV is operated by the UD and performs the following actions autonomously in the distributed manner. (I) Flying between the initial position, at which the UAV can communicate directly with the UD, and the sensing region assigned to the UAV (II) Acquiring image data (still or moving images) of the sensing region assigned to the UAV. (III) Staying at the initial position and performing the following actions in parallel: (a) analyzing a part of collected image data with the computational power of the UAV and (b) delegating the analysis of the rest of the data to the ES. (IV) Reporting results obtained from the analysis of image data to the UD soon after it has been completed. Note that we assume that UAVs cannot perform any analysis while flying; computational resources of UAVs are fully used for flight control and image acquiring during the flight.Each UAV repeats all the actions (I) to (IV). We call one action (I) to (IV) of some UAV one round.

The ES is placed closely to the UD and works to perform the analysis of a part of image data received from UAVs. Like UAVs do, soon after the ES has completed the analysis, it reports the results to the UD.

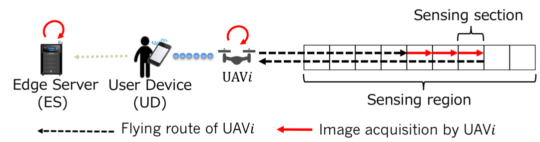

Fig. 2. System model for problem formulation

2) System flow: In the system we assume in this paper, the schedules of flying, acquiring, and analyzing of UAVs are determined through the following steps:

(1) Check if there is one or more UAVs the schedules of which have not been determined yet.
(2) Pick one of the unscheduled UAVs and label it as UAV $i (i = 1, 2, 3 \cdots)$, if step (1) is yes.
(3) Refer to the information about the schedules of UAVs $i-1$, $i-2$, $i-3$, $\cdots$, which were scheduled before UAV i.
(4) Determine the schedule of UAV i by a scheduling method, which will be described later.
(5a) Increment i to $i+1$. Go back to step (1).
(5b) UAV i starts its operation based on the determined schedule and will be added to the list of unscheduled UAVs after completing all the actions (I) to (IV) mentioned in Section III-A1.

Note that (5a) and (5b) are executed in parallel. At step (4), the scheduling method requires some time for calculating the schedule of UAV i. The calculating time depends on the complexity of the scheduling method. Therefore, the complexity of the scheduling method should not be complicated. However, from the second round of the scheduling for a UAV, the calculation can be done in advance while the UAV is performing step (5b) because all the previous schedules before the UAV have been determined already and the information of all the previous schedules are available. When the ES receives a computational task from a UAV via the UD, the ES puts it to the waiting queue. The ES processes those computational tasks in the first-in first-out (FIFO) manner and reports the result to the UD immediately after finishing each computational task.

B. Proposed scheduling method

We assume the system model shown in Figure 2, in which sensing sections are placed on the one-dimensional line and their sizes are identical. Sensing sections are assigned to UAVs from the one closest to the initial position and only an image is acquired at each sensing section. These assumptions allow us to simply deal with the sensing range of each UAV as the number of images acquired by them. We also assume that, if the ES or the communication channel of UD is still used by previously scheduled UAVs (UAVs $1, 2, \cdots i-1$), UAV i has to wait in the FIFO manner until their operations are completed. This also means that the operation of UAV i does not affect the operations of UAVs $1, 2, \cdots i-1$.

1) Utility: This section presents the mathematical formula of the utility function. The utility function of UAV i in the proposed method, U^i, is given as:

TABLE I
DEFINITION OF NOTATION

	Description
N^i	No. of images acquired by UAV i
N_u^i	No. of images processed by UAV i in N^i
N_e^i	No. of images delegated from UAV i to ES
T_{ng}	Flying time per sensing section
T_g	Image acquisition time per sensing section
T_f	Flying time from initial position to left-end of sensing sections
$T_{u,d}^i(N^i, N_u^i)$	Transmission waiting time from UAV i to UD
$T_{d,e}^i(N^i, N_u^i)$	Transmission waiting time of UAV i's data from UD to ES
$T_e^i(N^i, N_u^i)$	Processing waiting time at ES
$\mu_{u,d}$	Transmission speed from UAV i to UD in no. of images per unit time
$\mu_{d,e}$	Transmission speed from UD to ES in no. of images per unit time
P_u^i	Processing speed at UAV i in no. of images per unit time
P_e	Processing speed at ES in no. of images per unit time

$$U^i = \frac{\eta^i}{\Delta t^i} \tag{1}$$

where η^i means the efficiency of obtaining results from analyzed data and Δt^i is the interval of obtaining the results. They are called acquisition efficiency and acquisition interval, respectively, and defined as:

$$\eta^i = \frac{N^i}{t_{fin}^i - t_{start}^i} \tag{2}$$

$$\Delta t^i = t_{fin}^i - t_{fin}^{i-1} \quad (t_{fin}^0 = 0, t_{fin}^i \geq t_{fin}^{i-1}) \tag{3}$$

where N^i means the number of images acquired by UAV i, t_{start}^i is the flight start time of UAV i, and t_{fin}^i is the time when processing N^i images is finished. The utility function in defined by formula (1) suggests that, as the acquisition efficiency and interval become higher and shorter, the system works better for users. The reason why it is reasonable is because, in surveillance scenarios, users would expect to obtain as many pieces of information as possible during a certain period, while more updated information would be more valuable for them.

2) Problem formulation: This section discusses the problem formulation of the proposed scheduling method. Table I lists the definition of the notation we use. In this table, N^i, N_u^i, and N_e^i are variable. Using the notation, the problem formulation is described as below:

$$\underset{N^i, N_u^i}{\arg\max} \quad U^i = \frac{\eta^i}{\Delta t^i} (= \frac{N^i}{t_{fin}^i - t_{start}^i} \frac{1}{t_{fin}^i - t_{fin}^{i-1}}) \tag{4}$$

$$s.t. \quad N_{MIN}^i \leq N^i, \tag{5}$$

where N_{MIN}^i means that UAV i has to acquire at least N_{MIN}^i images so as not to complete its actions earlier than the previous UAV, UAV $i-1$: $t_{fin}^i \geq t_{fin}^{i-1}$. This formulation suggests that N^i and N_u^i must be determined so that the utility function, U^i, is maximized.

t_{fin}^i in formula (4) is represented as:

$$t_{fin}^i(N^i, N_u^i) = t_{start}^i + 2(T_f + \sum_{j=1}^{i-1} N^j T_{ng}) + N^i(T_g + T_{ng}) + \max(\frac{N_u^i}{P_u^i}, T_{u,d}^i(N^i, N_u^i) + \frac{N_e^i}{\mu_{u,d}} + T_{d,e}^i(N^i, N_u^i) + \frac{N_e^i}{\mu_{d,e}} + T_e^i(N^i, N_u^i) + \frac{N_e^i}{P_e}) \tag{6}$$

Eliminating N_e^i from formula (6) using $N^i = N_u^i + N_e^i$, $t_{fin}^i(N^i, N_u^i)$ becomes a function of two variables, N^i and N_u^i. According to formula (6), $t_{fin}^i - t_{start}^i$ is equal to the sum of flight time, transmission time, and processing time of UAV i. The second and third terms in the right side of formula (6) represent the flight time outside the sensing range of UAV i and the sum of the image acquisition time and the flight time within the sensing range assigned to UAV i, respectively. The max function of the fourth term in the right side of formula (6) is the processing time of N^i images, which is equal to the longer one of the image processing time at the UAV i or the total consumed time for image transmission from UAV i to the ES and the image processing at the ES. $T_{u,d}^i(N^i, N_u^i)$, $T_{d,e}^i(N^i, N_u^i)$, and $T_e^i(N^i, N_u^i)$ in the right side of formula (6) are waiting times for UAV i. As we mentioned before, if previous UAVs (UAV1,UAV2,$\cdots$, UAV$i-1$) are still using the communication channel of the UD or the computational resource of the ES, UAV i has to wait for a certain waiting time until all the transmission and processing tasks have been completed. That is, t_{fin}^{i-1}, which is the time when processing N^{i-1} images acquired by UAV $i-1$ is finished, is not affected by the operation of UAV i and can be dealt as a constant value in the scheduling of UAV i. Note that we assumed, since the size of output data obtained after processing at UAVs and the ES is quite small, transmission time of those output data is negligible.

N_{MIN}^i in formula (5) is the specific value of N^i that satisfies the following condition:

$$\underset{N^i, N_u^i}{\arg\min} \quad t_{fin}^i(N^i, N_u^i) \tag{7}$$

$$s.t. \quad t_{fin}^i(N^i, N_u^i) \geq t_{fin}^{i-1}(N_u^i \in \mathbb{N} \mid 0 \leq N_u^i \leq N^i). \tag{8}$$

Here, suppose that N_u^i is determined so as to minimize $t_{fin}^i(N^i, N_u^i)$ for a given N^i. For such N_u^i, N_{MIN}^i is the minimum integer among possible values of N^i that satisfy Formula (8). By setting N_{MIN}^i so, as long as N_u^i is chosen so as to satisfy $0 \leq N_u^i \leq N^i$, the optimal N^i in formula (4) can be determined among the possible values of N^i that satisfy $U^i(=\frac{\eta^i}{\Delta t^i}) > 0$.

C. feature of proposed scheduling method

The feature of proposed scheduling method is listed below.

- It is user-centric
- The user can collect as many pieces of information as possible for a certain period
- The user can obtain Fresh information of each sensing section

TABLE II
SIMULATION PARAMETERS

Parameters	value
Flying speed of UAVs	15 m/s
Distance between initial position and left-end of sensing block	200 m
Size of each sensing section	5 m
Size of image	100 kbytes
Consumed time for acquiring one image	2 s
Consumed time for processing one image at UAVs	2 s
Consumed time for processing one image at ES	200 ms
Transmission rate of communication channel	100 Mbps
No. of UAVs	5

- The user can optimally use it based on the processing capacity of each UAV and the ES
- It can immediately deal with the breakdown of UAV and increase in number of UAV, as well as the ES, since it schedules UAV and ES sequentially.
- it is applicable to the two-dimensional area, though the theory of it is based on the one-dimensional model, as will be described in Section V

IV. Performance evaluation

A. Simulation scenario

A simulation study was performed to validate the proposed scheduling method. We considered a surveillance scenario in which a rescue team uses the multi-UAV system illustrated in Figure 1 to find missing people in an area where humans and ground vehicles cannot easily step into. For simplification of the performance evaluation, we used the one-dimensional model in Figure 2 as the simulation model. Our simulation adopted the proposed scheduling method described in Section **??** and performed every step of the system flow described in Section III-A2.

B. Simulation description

The parameters used in our simulation are listed in Table II. Considering the realistic specification of a recently commercialized UAV [22], we set the flying speed of UAVs to 15 m/s. The size of images was set to 100 kbytes, which corresponds to the one in the dataset called PASCAL VOC 2007 used in [23]. The consumed times for processing one image at UAVs and the ES are set corresponding to the consumed time for object recognition using GPU and CPU reported in [23], respectively. The transmission rates of communication channel from UAVs to the UD and from the UD to the ES are set 100 Mbps, which is similar to the effective throughput of IEEE802.11n [24].

C. Evaluation metric and compared methods

In our performance evaluation, we used the following two evaluation metrics. The first one is 'elapsed time from start time' for each image, which is the elapsed time since the first UAV starts flying until the result about each image is obtained by the UD. This metric is important for the rescue team because they need to know the information about each sensing section as soon as possible to know whether missing people are there or not. The second one is 'elapsed time after acquired' for each image, which is the elapsed time since an image is acquired at the corresponding sensing section until the result about the image is obtained by the UD. This metric is also valuable for the rescue team because it indicates the freshness of the information about each sensing section; the less updated information, the less reliable for them in searching missing people.

We compared the following proposed methods with three types of computing with fixed method, which are different from each other in how to determine N^i.

· **Proposed (UAV&ES)**
It adopts the proposed scheduling method described in Section III-B. Images are processed at both UAVs and the ES.

· **Proposed (UAV-only)**
It adopts the proposed scheduling method described in Section III-B but images are processed at only UAVs.

· **Proposed (ES-only)**
It adopts the proposed scheduling method described in Section III-B but images are processed at only the ES.

· **Fixed**
It simply assigns a fixed number of sensing sections to each UAV uniformly. Images are processed at both UAVs and the ES.

Note that, the proposed scheduling method finds out the local optimal solution, N_l^i, as we mentioned the datail in APPENDIX A. In our simulation, the range of local searching in the proposed scheduling method was set enough wide so that it can ensure that the local optimal solution equals to the true optimal solution. In addition, we assumed that the consumed time for finding out the local optimal solution is negligible; since the complexity of the scheduling algorithm is quite simple, the calculation can be finished in advance while the UAV is flying in the previous round.

D. Results

In this section, we first compare the three types of computing using the proposed scheduling method defined in Section IV-C: Proposed (UAV&ES), Proposed (UAV-only), and Proposed (ES-only). Then, we compare the best one out of them with the fixed method defined in Section IV-C.

1) Comparison in three types of computing: Figure 3 plots the elapsed time from the start time about each image versus the distance of the sensing section at which the image is acquired from the initial position. As we see in the figure, the elapsed times in all the proposed methods keep almost constant and then increase for the longer distance of sensing sections. However, Proposed (ES-only) worked a little worse than Proposed (UAV&ES) and Proposed (UAV-only) in terms of this metric.

On the other hand, Figure 4 plots the elapsed time after acquired about each image. The horizontal axis of this figure is

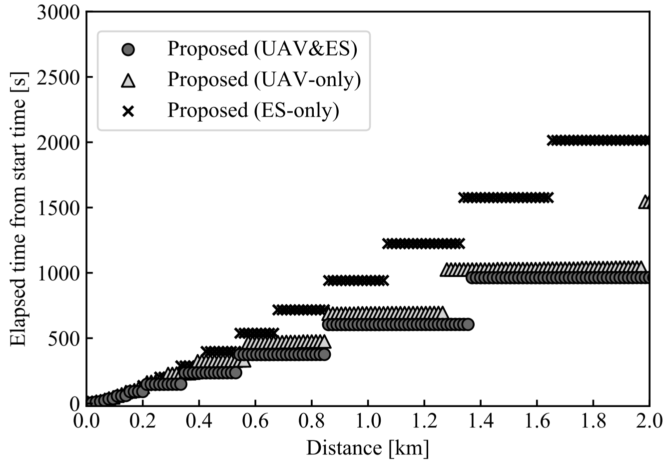

Fig. 3. Elapsed time from start time vs. Distance of sensing sections. Proposed (UAV&ES), Proposed (UAV-only), and Proposed (ES-only) are compared.

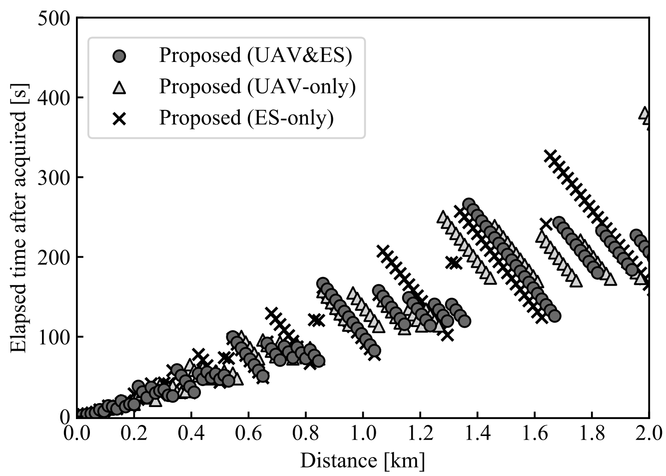

Fig. 4. Elapsed time after acquired vs. Distance of sensing sections. Proposed (UAV&ES), Proposed (UAV-only), and Proposed (ES-only) are compared.

the same as the one in Figure 3. In this figure, the elapsed time after acquired decreases with some regular pattern, against the distance of the sensing sections. In a part of the areas:0.25-0.35km, 0.65-0.75km, 0.85-0.90km, 1.2-1.4km, 1.9-2.0km, Proposed (ES-only) and Proposed (UAV-only) worked better than Proposed (UAV&ES) in terms of this metric. On the other hand, in all the rest areas (most of the whole areas), Proposed (UAV&ES) worked better than Proposed (UAV-only) and Proposed (ES-only).

From the above result, the proposed method is adaptable to various situations of given computational performance. It also suggests that Proposed (UAV&ES) worked best among the three types of computing using the proposed scheduling methods thanks to its integrated computational power of UAVs and the ES. There, in the next section, we only focus on Proposed (UAV&ES) without considering Proposed (UAV-only) and Proposed (ES-only).

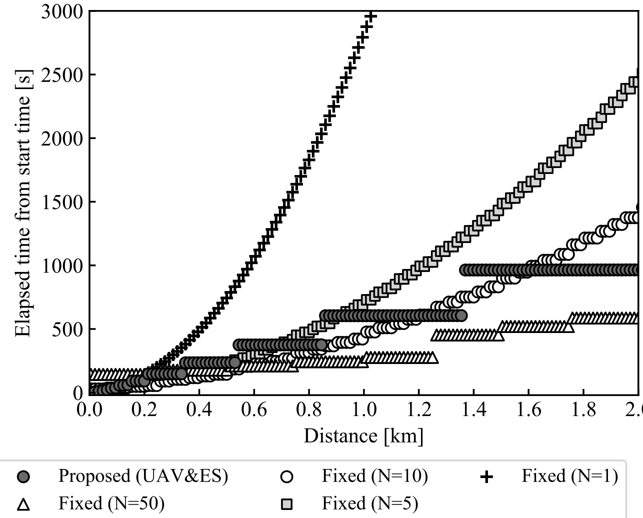

Fig. 5. Elapsed time from start time vs. Distance of sensing sections. Proposed and Fixed are compared.

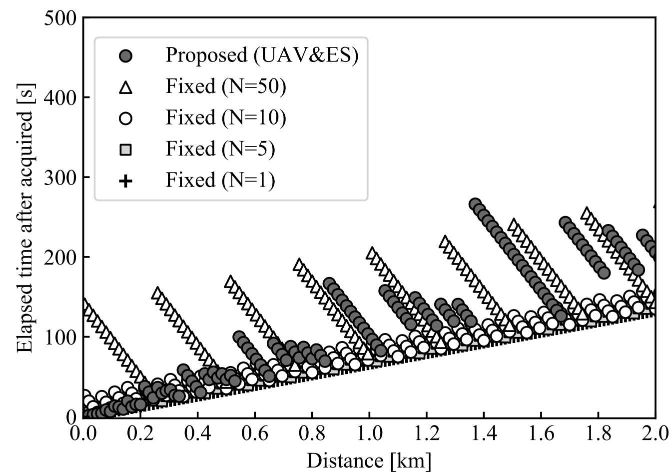

Fig. 6. Elapsed time after acquired vs. Distance of sensing sections. Proposed and Fixed are compared.

2) Comparison with fixed method: In this section, we compare Proposed (UAV&ES) with Fixed defined in Section IV-C. The vertical and horizontal axes in Figures 5 and 6 are the same as the ones in Figures 3 and 4, respectively. We examined the Fixed with N^i = 1, 5, 10, and 50.

In Figure 5, for longer distance of sensing sections, the elapsed time from start time monotonically increases in all the methods. However, in the Fixed, as N^i was set larger, the elapsed time increased more gradually. Proposed (UAV&ES) performed similarly to the Fixed with $N^i = 10$.

On the other hand, in Figure 6, the elapsed time after acquired decreases with some regular pattern in all the methods. However, in the Fixed, as N^i was set smaller, the elapsed time became shorter. Proposed (UAV&ES) worked between the Fixed with $N^i = 10$ and $N^i = 50$.

From the overall observation shown above, in the Fixed,

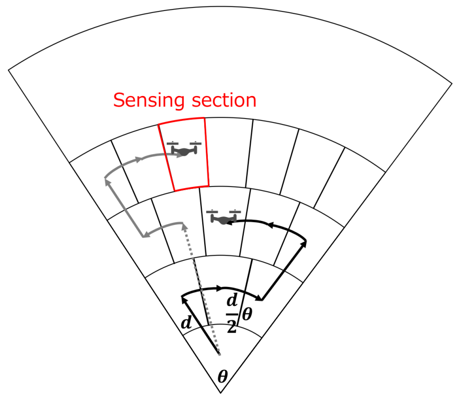

Fig. 7. Sensing region of two-dimensional model

$N^i = 10$ should be most reasonable in terms of both types of elapsed time. Since Proposed (UAV&ES) worked similarly to the Fixed with $N^i = 10$ without requiring any parameter setting unlike the Fixed, we can conclude that Proposed (UAV&ES) works best in this evaluation scenario.

V. Extension to two-dimensional model

In this section, we mention that the proposed scheduling method described in Section III-B can be applied not only to the one-dimensional model in Figure 2 but also directly to the two-dimensional model. There are two assumptions in which the proposed scheduling method can be extended to the two-dimensional model shown in Figure 7 :

(1) Assuming fan-shaped sensing region, split the region so that each sensing section range is constant
(2) Each UAV executes sensing on the zigzag in order from the area closest to the center like [8]

As shown in Figure 7, assuming that the vertical width of each partition is d and the central angle of the sensing region is θ [rad], the distance between each section when UAV moves in the direction opposite to the center of the region is d and the distance between each section when moving on the circumference is $\frac{1}{2}d\theta$. Therefore, when $\theta = 2$ [rad], all the distance between each section are equal as in Figure 2 and the proposed scheduling method described in Section III-B can be directly applicable to the Figure 7.

VI. Conclusion

This paper proposed a scheduling method of multi-UAV search system that considers processing time of the acquired image data and data transfer time in areas where humans and ground vehicles cannot easily step into like disaster-damaged areas. In this paper, we first showed the system model, which consists of a user device, multiple UAVs, and an edge server, and mentioned the sytem flow. We then presented the problem formulation of the proposed scheduling method that maximizes the user's utility, which is calculated from the efficiency of obtaining results from analyzed data and the interval of obtaining the results, by using the one-dimensional model where sensing sections are placed on the one-dimensional line and their sizes are identical. A simulation was performed to verify that the proposed method works well to ensure the freshness of individual obtained piece of information while delivering as many pieces of information as possible for a certain period. The results indicated that the proposed method works better than the conventional fixed methods, in terms of two metrics: i) elapsed time from start time and ii) elapsed time after acquired for each image. For a more practical evaluation, in our future work, we will include prototype implementation and experiment.

Appendix A
Optimal solution

This section discusses a solution of the problem formulation described in section III-B, which is used in our scheduling method. It takes long time to solve formulas (4) and (5) due to their computational complexities, the calculation for scheduling could be non-negligible overhead in the system; UAVs have to wait to start flying until their schedules have been determined. Therefore, to simplify the calculation of formulas (4) and (5), our scheduling method first supposes that all the waiting times for UAV i are equal to zero and obtains an approximated solution, N^i_{th}. Then, by searching locally around N^i_{th}, our scheduling method considers all the waiting times in formulas (4) and (5) and finds out the local optimal solution, N^i_l. The following part explains the way of finding out N^i_{th}. First, we set all the waiting times to zero. Then, we replace the second and fourth terms in formula (6) with $2F$ and M, respectively. Then, by substituting t^i_{fin} in (6) to formula (1), we obtain $\frac{\eta^i}{\Delta t^i}$ as below:

$$\frac{\eta^i}{\Delta t^i} = \frac{N^i}{N^i(T_g + T_{ng}) + 2F + M} \times \frac{1}{N^i(T_g + T_{ng}) + 2F + M + t^i_{start} - t^{i-1}_{fin}} \tag{9}$$

where, by regarding N^i as a constant, only M is a variable and the value of $\frac{\eta^i}{\Delta t^i}$ varies dependently on the values of N^i_u and N^i_e. Since $\frac{\eta^i}{\Delta t^i}$ is always positive, M takes the minimum when $\frac{\eta^i}{\Delta t^i}$ takes the maximum. Although N^i, N^i_u, and N^i_e are integers, here we deal with them as real numbers. Considering $N^i = N^i_u + N^i_e$, on the assumption that $\frac{N^i_u}{P^i_u}$ equals to $\frac{N^i_e}{\mu_{u,d}} + \frac{N^i_e}{\mu_{d,e}} + \frac{N^i_e}{P_e}$, we can obtain the value of N^i_u and N^i_e that satisfy $0 \leq N^i_u$ and $N^i_e \leq N^i$ as follows:

$$N^i_u = \frac{P^i_u(\mu_{d,e}P_e + \mu_{u,d}P_e + \mu_{u,d}\mu_{d,e})}{\mu_{u,d}\mu_{d,e}P_e + P^i_u(\mu_{d,e}P_e + \mu_{u,d}P_e + \mu_{u,d}\mu_{d,e})} N^i \tag{10}$$

$$N^i_e = \frac{\mu_{u,d}\mu_{d,e}P_e}{\mu_{u,d}\mu_{d,e}P_e + P^i_u(\mu_{d,e}P_e + \mu_{u,d}P_e + \mu_{u,d}\mu_{d,e})} N^i \tag{11}$$

When M takes the minimum value, $\frac{N^i_u}{P^i_u}$ is theoretically equal to $\frac{N^i_e}{\mu_{u,d}} + \frac{N^i_e}{\mu_{d,e}} + \frac{N^i_e}{P_e}$, while N^i_u and N^i_e become formula (10) and (11), respectively. As N^i becomes larger, $\frac{N^i_u}{P^i_u}$ is closer to

$\frac{N_e^i}{\mu_{u,d}} + \frac{N_e^i}{\mu_{d,e}} + \frac{N_e^i}{P_e}$. Thus, $\frac{N_u^i}{P_u^i} = \frac{N_e^i}{\mu_{u,d}} + \frac{N_e^i}{\mu_{d,e}} + \frac{N_e^i}{P_e}$ is established. As a result, $\frac{\eta^i}{\Delta t^i}$ in formula (9) is given as:

$$\frac{N^i}{R^2(N^i)^2 + (4F + t_{start}^i - t_{fin}^{i-1})RN^i + 2F(2F + t_{start}^i - t_{fin}^{i-1})} \tag{12}$$

$$\left(R = T_g + T_{ng} + \frac{\mu_{d,e}P_e + \mu_{u,d}P_e + \mu_{u,d}\mu_{d,e}}{\mu_{u,d}\mu_{d,e}P_e + P_u^i(\mu_{d,e}P_e + \mu_{u,d}P_e + \mu_{u,d}\mu_{d,e})}\right)$$

To sketch formula (12), by differentiating it by N^i, we obtain:

$$\frac{-R^2(N^i)^2 + 2F(2F + t_{start}^i - t_{fin}^{i-1})}{\{R^2(N^i)^2 + (4F + t_{start}^i - t_{fin}^{i-1})RN^i + 2F(2F + t_{start}^i - t_{fin}^{i-1})\}^2} \tag{13}$$

When $t_{start}^i \leq t_{fin}^{i-1} - 2F$, formula (12) decreases monotonically as the value of N^i increases and takes the maximum when N_{th}^i is N_{MIN}^i. When $t_{start}^i > t_{fin}^{i-1} - 2F$, $\frac{\eta^i}{\Delta t^i}$ is a convex function taking the maximum when N^i is $\frac{\sqrt{2F(2F+t_{start}^i - t_{fin}^{i-1})}}{R}$. Note that N^i is chosen so that the denominator of formula (12) does not become zero. Through the above procedures, we can obtain N_{th}^i as follows:

$$N_{th}^i = \begin{cases} \frac{\sqrt{2F(2F+t_{start}^i - t_{fin}^{i-1})}}{R} & (N_{MIN}^i \leq \frac{\sqrt{2F(2F+t_{start}^i - t_{fin}^{i-1})}}{R}) \\ N_{MIN}^i & (\frac{\sqrt{2F(2F+t_{start}^i - t_{fin}^{i-1})}}{R} < N_{MIN}^i) \end{cases} \tag{14}$$

ACKNOWLEDGMENT

This work was partly supported by JSPS KAKENHI Grant Number JP17H01732.

REFERENCES

[1] Debarati Guha-Sapir, Philippe Hoyois, Pasacline Wallemacq and Regina Below,“Annual Disaster Statistical Review 2016,”*Centre for Research on the Epidemiology of Disasters*,2016

[2] Japan Ministry of Defense, “Lessons from the Great East Japan Earthquake,” http://www.mod.go.jp/e/publ/w_paper/pdf/2012/30_Part3_Chapter1_Sec3.pdf, 2012

[3] T. Andre, K. Hummel, A. Schoellig, E. Yanmaz, M. Asadpour, C. Bettstetter, P. Grippa, H. Hellwagner, S. Sand and S. Zhang, “User devicelication-driven design of aerial communication networks, ” *IEEE Commun. Mag.*, vol. 52, no. 5, pp. 129-137, 2014

[4] M. Erdelj, and N. Enrico, “UAV-assisted disaster management: User devicelications and open issues, ” *2016 International Conference on Computing, Networking and Communications (ICNC)*,pp1-5, 2016

[5] M. Di Felice, A. Trotta, L. Bedogni, K. R. Chowdhury and L. Bononi, “Self-organizing aerial mesh networks for emergency communication, ” *Personal, Indoor, and Mobile Radio Communication (PIMRC), IEEE 25th Annual International Symposium on*, pp. 1631-1636, 2014

[6] Armand Vervaeck and James Daniell,“Japan Tohoku tsunami and earthquake : The death toll is climbing again!, ” https://earthquake-report.com/2011/08/04/japan-tsunami-following-up-the-aftermath-part-16-june/, 2011

[7] P. Lanillos, S. K. Gan, E. Besada-Portas, G. Pajares and S. Sukkarieh, “Multi-UAV target search using decentralized gradient-based negotiation with expected observation,”*Information Sciences*, vol. 282, pp. 92-110, 2014.

[8] I. Maza, A. Ollero, “Multiple UAV cooperative searching operation using polygon area decomposition and efficient coverage algorithms, ”*Distributed Autonomous Robotic Sys-tems*, pp. 221-230, 2007.

[9] W. Meng, Z. R. He, R. Teo, L. xie, “Decentralized Search, Tasking and Tracking Using Multiple Fixed-Wing Miniature UAVs,” *11th IEEE International Conference on Control & Automation (ICCA)*, pp. 1345-1350, 2014

[10] C. Zhao, M. Zhu and H. Liang, “The Sustainable Tracking Strategy of Moving Target by Multi-UAVs in an Uncertain Environment, ” *2016 IEEE/CSAA International Conference on Aircraft Utility Systems (AUS)*, pp. 20-25, 2016

[11] M. Mirzaei, F. Sharifi, B. W. Gordon, C. A. Rabbath and Y. M.Zhang, “Cooperative multi-vehicle search and coverage problem in uncertain environments, ”*in Proceedings of the 50th IEEE Conference on Decision and Control and European Control Conference (CDCECC)*, pp. 4140-4145, 2011

[12] D. Bamburry, “Drones: Designed for product delivery,” *Design Management Review*, vol. 26, no. 1, pp. 40-48, 2015

[13] K. May,“Drones to deliver medicine and food? Drones for disaster relief? Why not?,”https://ideas.ted.com/6-ways-drones-can-be-used-for-good/, 2013

[14] A. Wada, T. Yamashita, M. Maruyama, T. Arai, H. Adachi and H. Tsuji, “A surveillance system using small unmanned aerial vehicle (UAV) related technologies,'' *NEC Technical Journal*,vol.8, no. 1, p68-72, 2015

[15] I. Bekmezci, O. K. Sahingoz, and S. Temel, “Flying Ad-Hoc Networks (FANETs): a survey, ” *Ad Hoc Networks*, vol. 11, no. 3, pp. 1254-1270, 2013

[16] J Sánchez-García, JM García-Campos, SL Toral, DG Reina and F Barrero, “An intelligent strategy for tactical movements of UAVs in disaster scenarios,'' *International Journal of Distributed Sensor Networks*, vol.12, no. 3, 2016

[17] S. Hayat, E. Yanmaz, T. X. Brown, and C. Bettstetter,“Multi-Objective UAV Path Planning for Search and Rescue, ” *ICRA Singapore*, 2017

[18] S. Ouahouah , T. Taleb, J. Song and C. Benzaid, “Efficient offloading mechanism for UAVs-based value added services,” *IEEE International Conference on Communications (ICC)*, 2017

[19] R. Valentino, W.-S. Jung and Y.-B. Ko,“Opportunistic Computational Offloading System for Clusters of Drones,” *International Conference on Advanced Communications Technology(ICACT)*, 2018

[20] N. H. Motlagh, M. Bagaa, and T. Taleb, “Uav-based iot platform: A crowd surveillance use case,*IEEE Communications Magazine*, vol.55, no.2, pp. 128-134, 2017

[21] M.-A. Messous1, A. Arfaoui, A. Alioua, S. -M. Senouci,“A Sequential Game Approach for Computation-Offloading in an UAV Network,'' *IEEE Global Communications Conference*, 2017

[22] Parrot SA, “PARROT BEBOP2 SO LIGHT YOU CAN TAKE IT ANYWHERE TO FILM IN FULL HD, ” http://www.parrot.com/usa/products/bebop2/, 2016

[23] S. Ren, K. He, R. Girshick, J. Sun, “Faster R-CNN: Towards real-time object detection with region proposal networks,” *In Advances in neural information processing systems*, pp. 91-99, 2015

[24] J. Li, Y. Fan, H. Chen, K. Xu, Y. Dai, F. Yin, Y. Ji, “Radio-over-fiber-based distributed antenna systems supporting IEEE 802.11 N/AC standards,” *Optical Communications and Networks (ICOCN), 2013 12th International Conference on. IEEE*, pp. 1-4, 2013