



7<sup>th</sup> July  
Východná, Slovakia

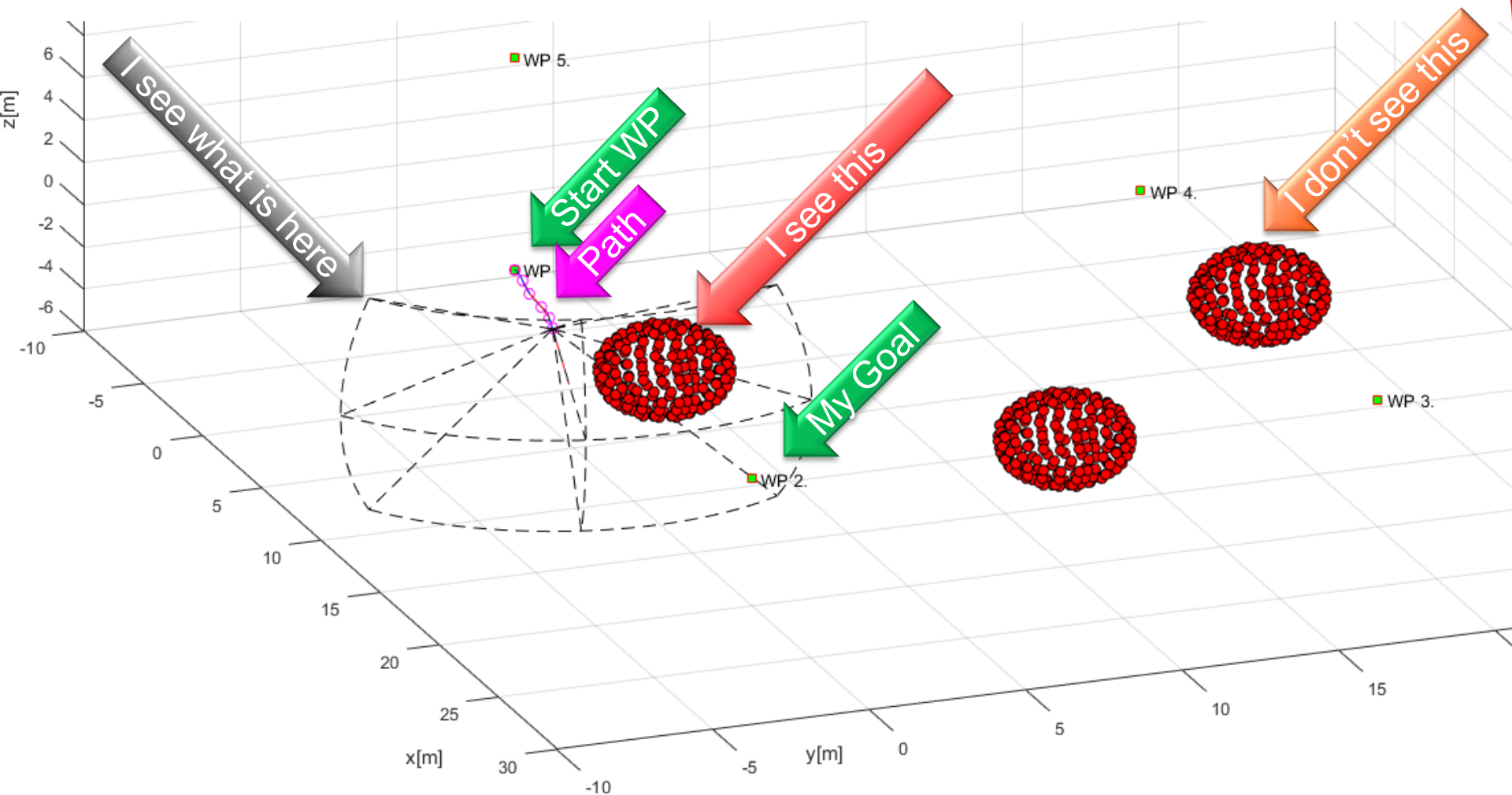
**THE STORY OF UAV WHICH WANT TO LIVE**  
Alojz Gomola, Advanced Technology Europe

**Honeywell**

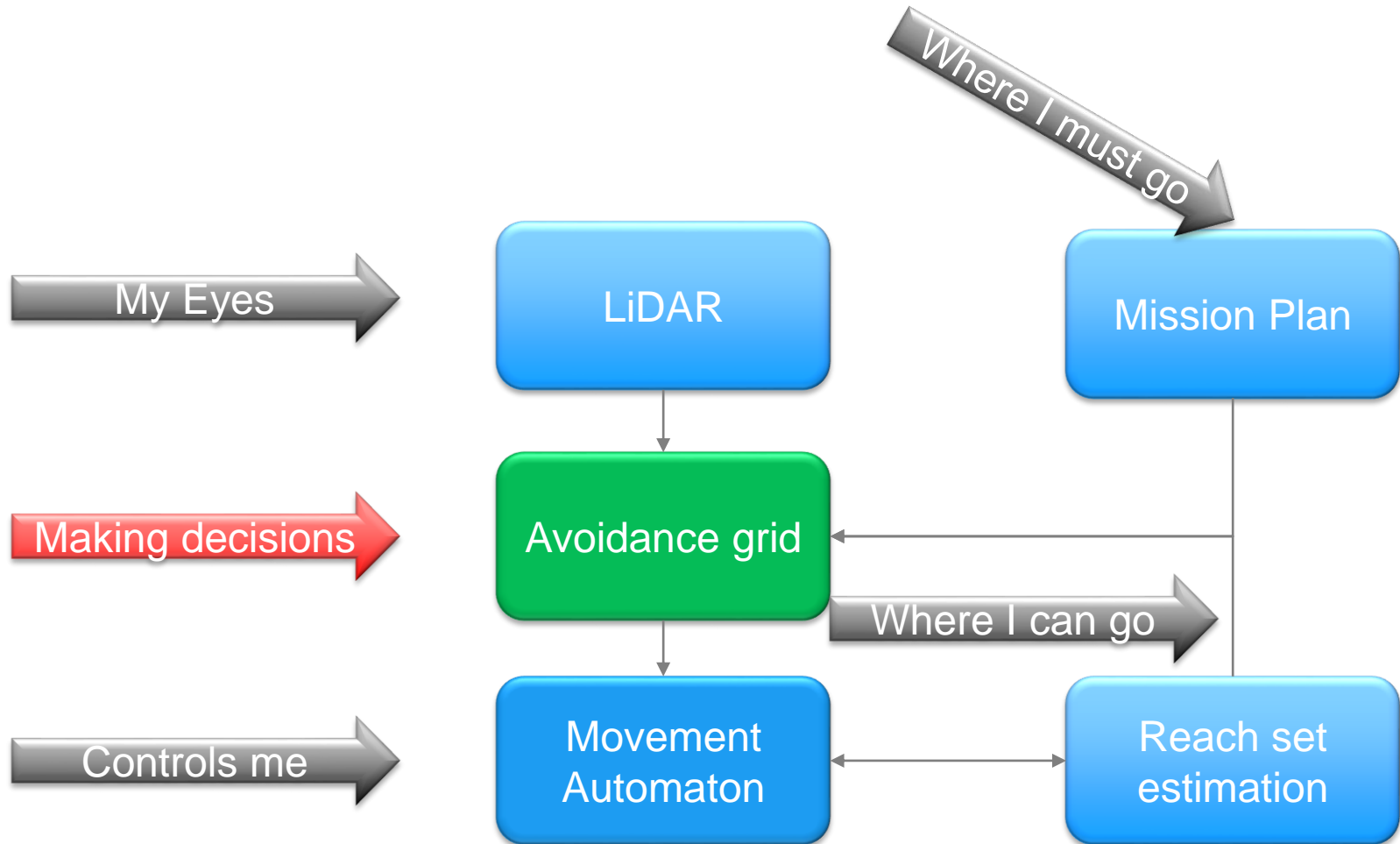
# I have a mission and I don't want to crash

- I am vehicle given by some equations  $\dot{x} = f(x, u)$
- My input signal is given by movement automaton  $\mathcal{MA}$ 
  - Key component is movement buffer which feeds me with commands
  - The containment of buffer is “Command chain”
- I can see with my sensors in some field of vision  $\mathcal{F}_{3D}(10m, 60^\circ, 45^\circ)$
- I can decide my next action after movement execution
  - I like to set some decision time  $t_i$  because I do not like calculations
- I did not crash, how is that possible ?
- Listen to a story of a elusive vehicle

# This is my mission

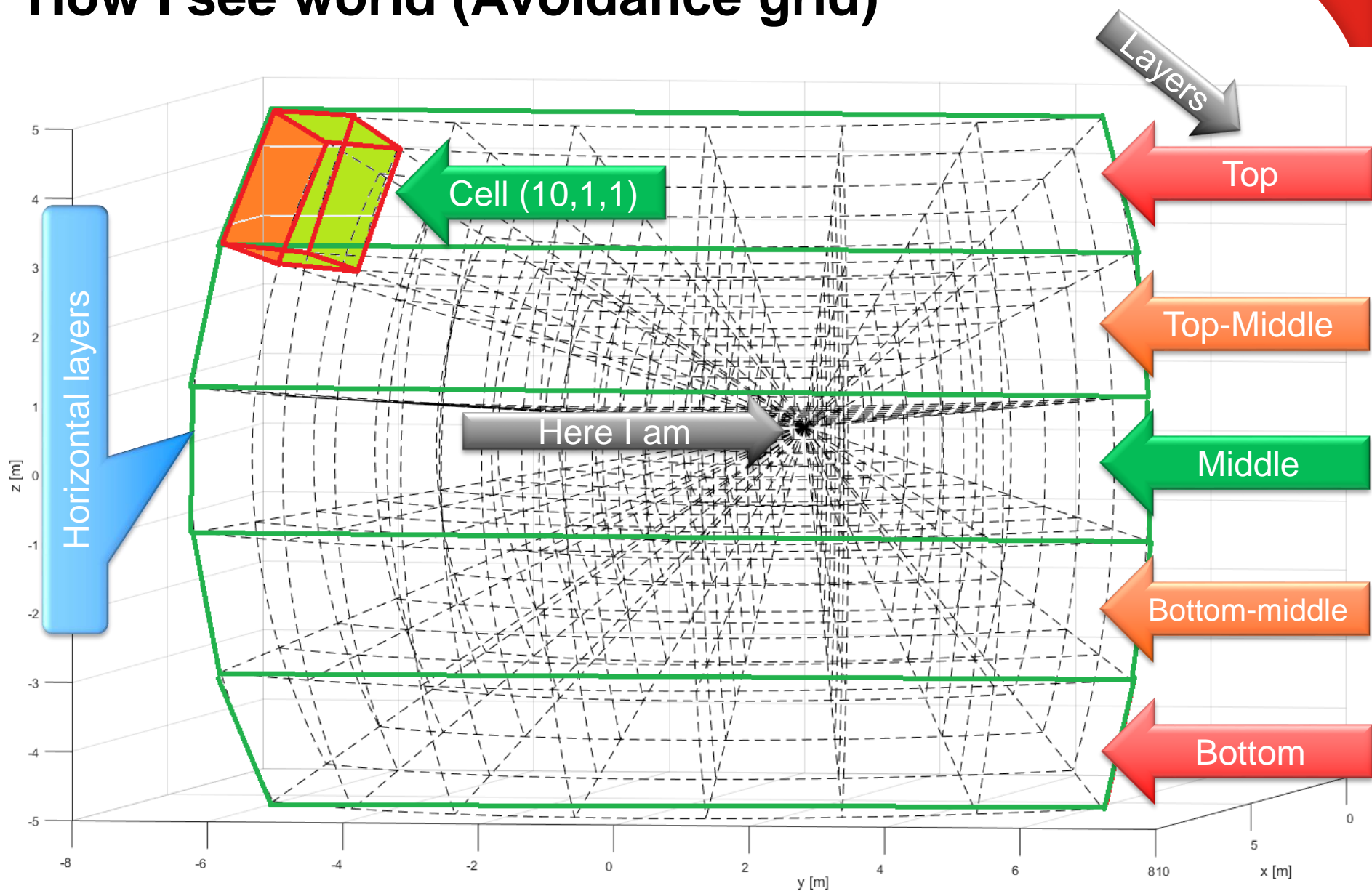


# This is my decision logic

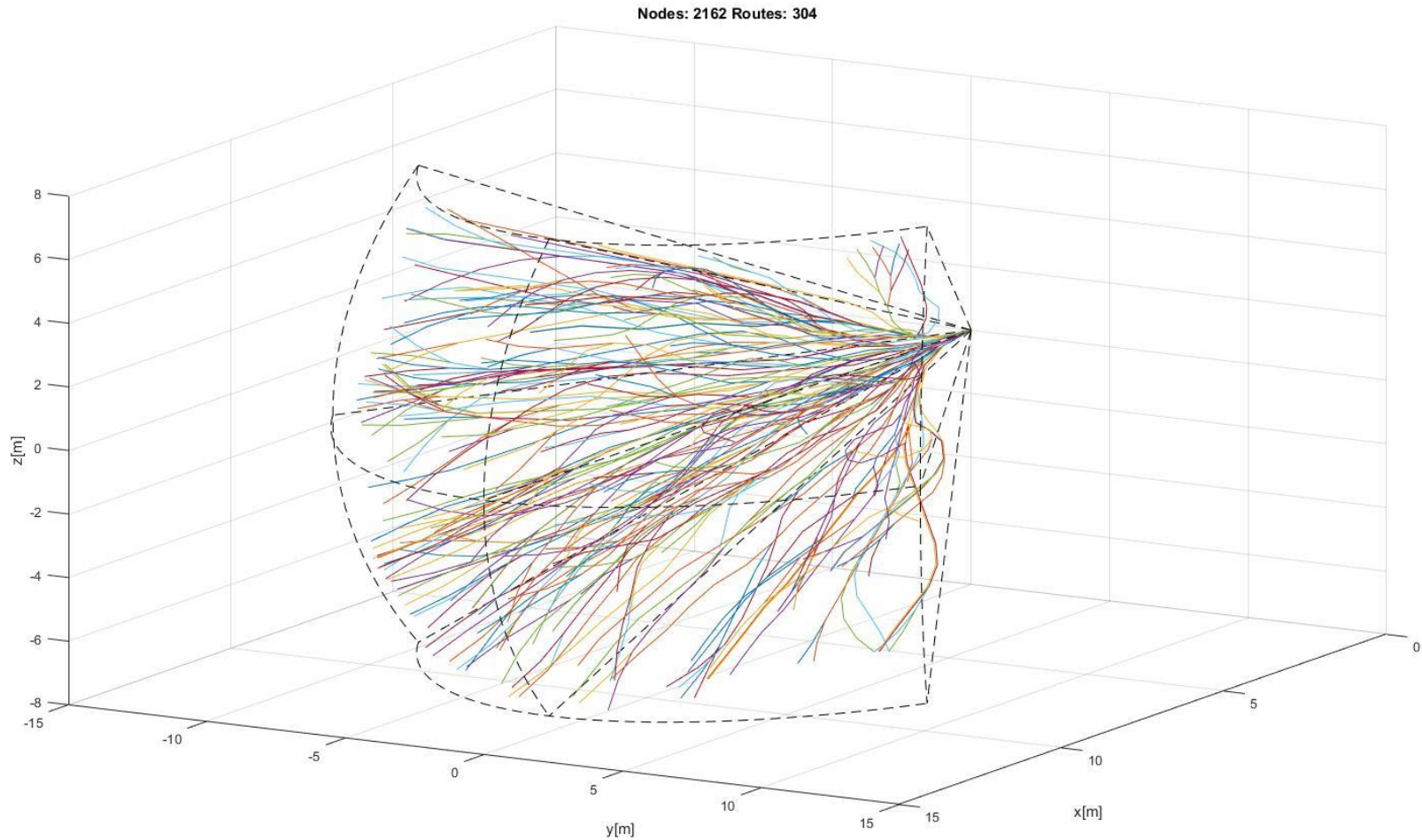




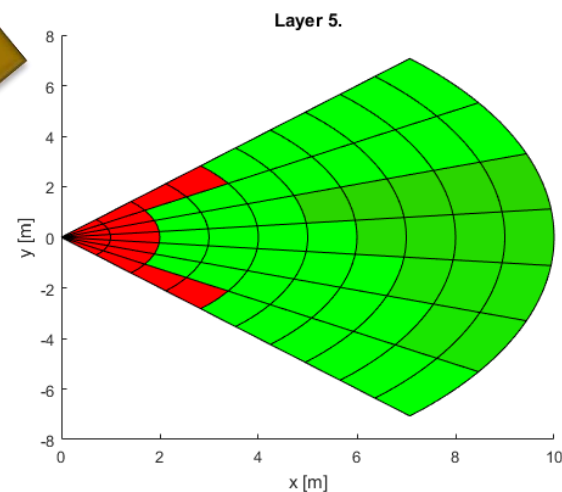
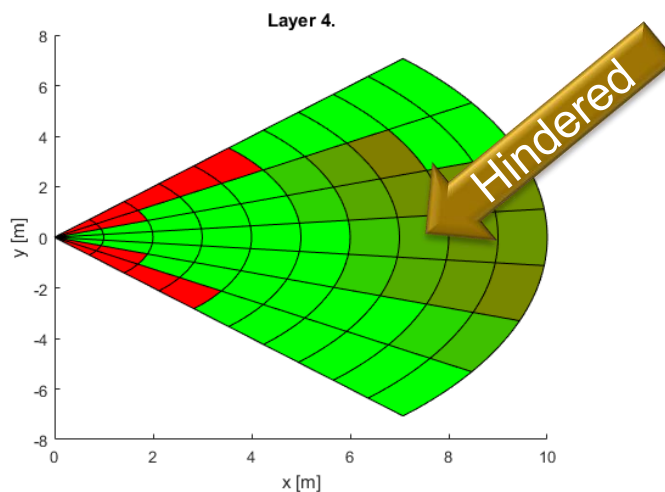
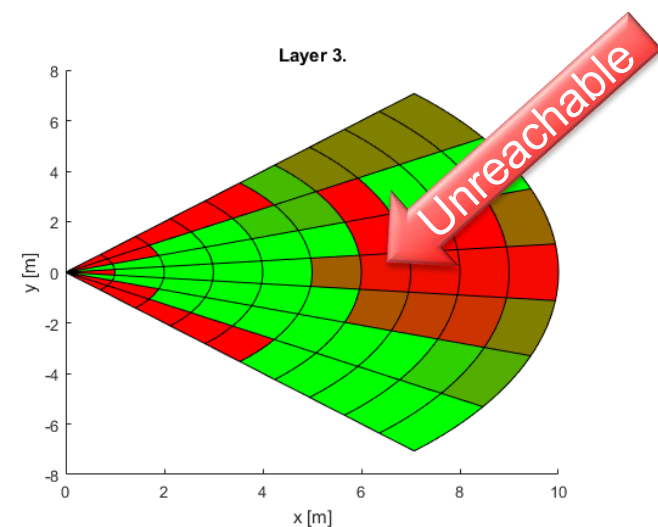
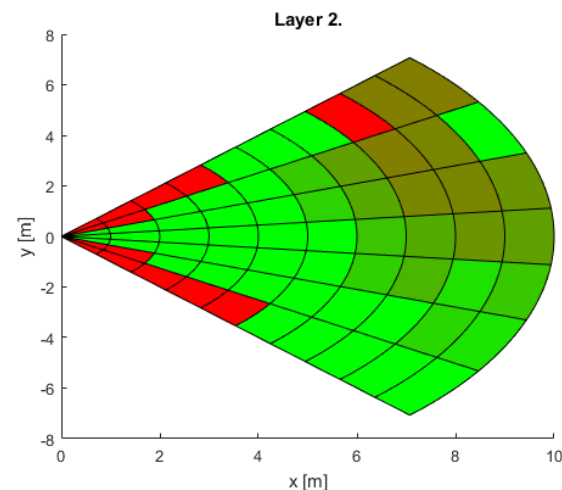
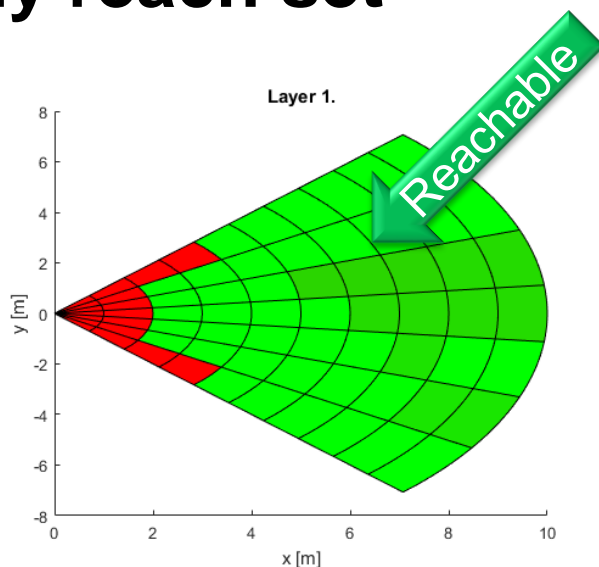
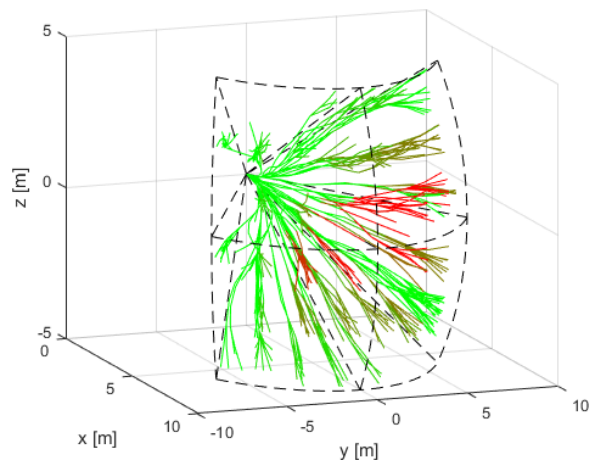
# How I see world (Avoidance grid)



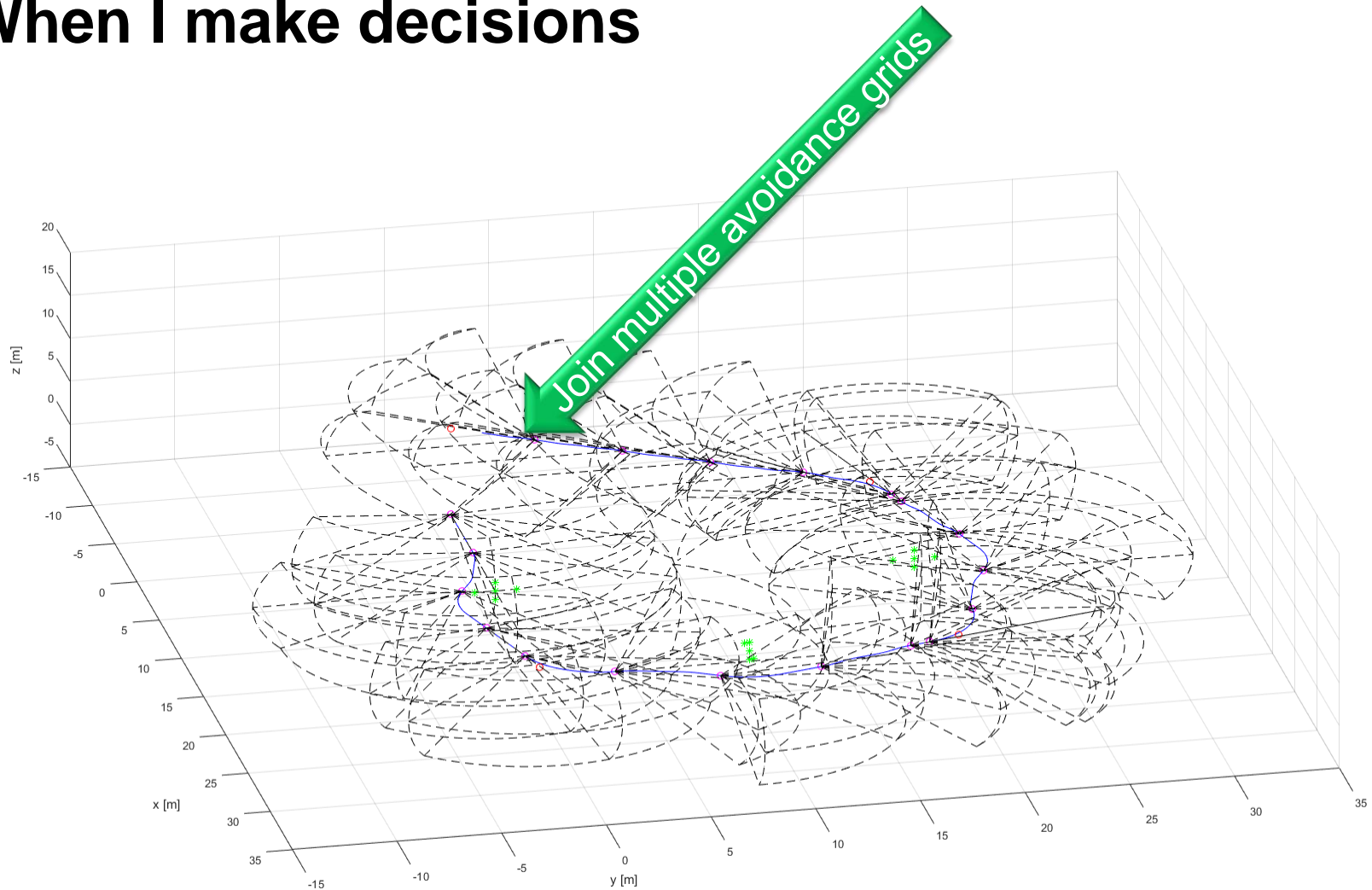
# Where I can fly in my FOV (My reach set)



# How I change my reach set

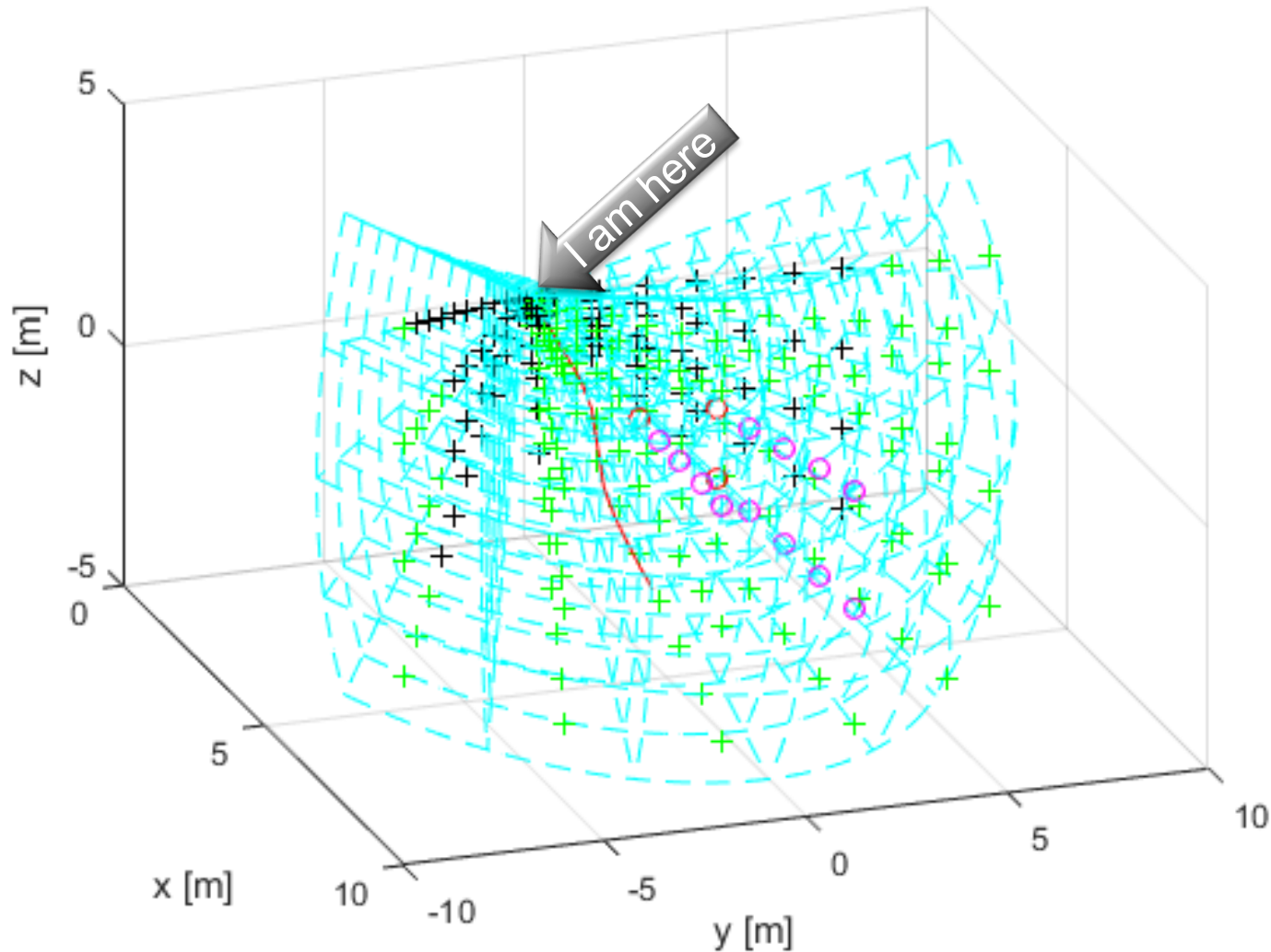


# When I make decisions

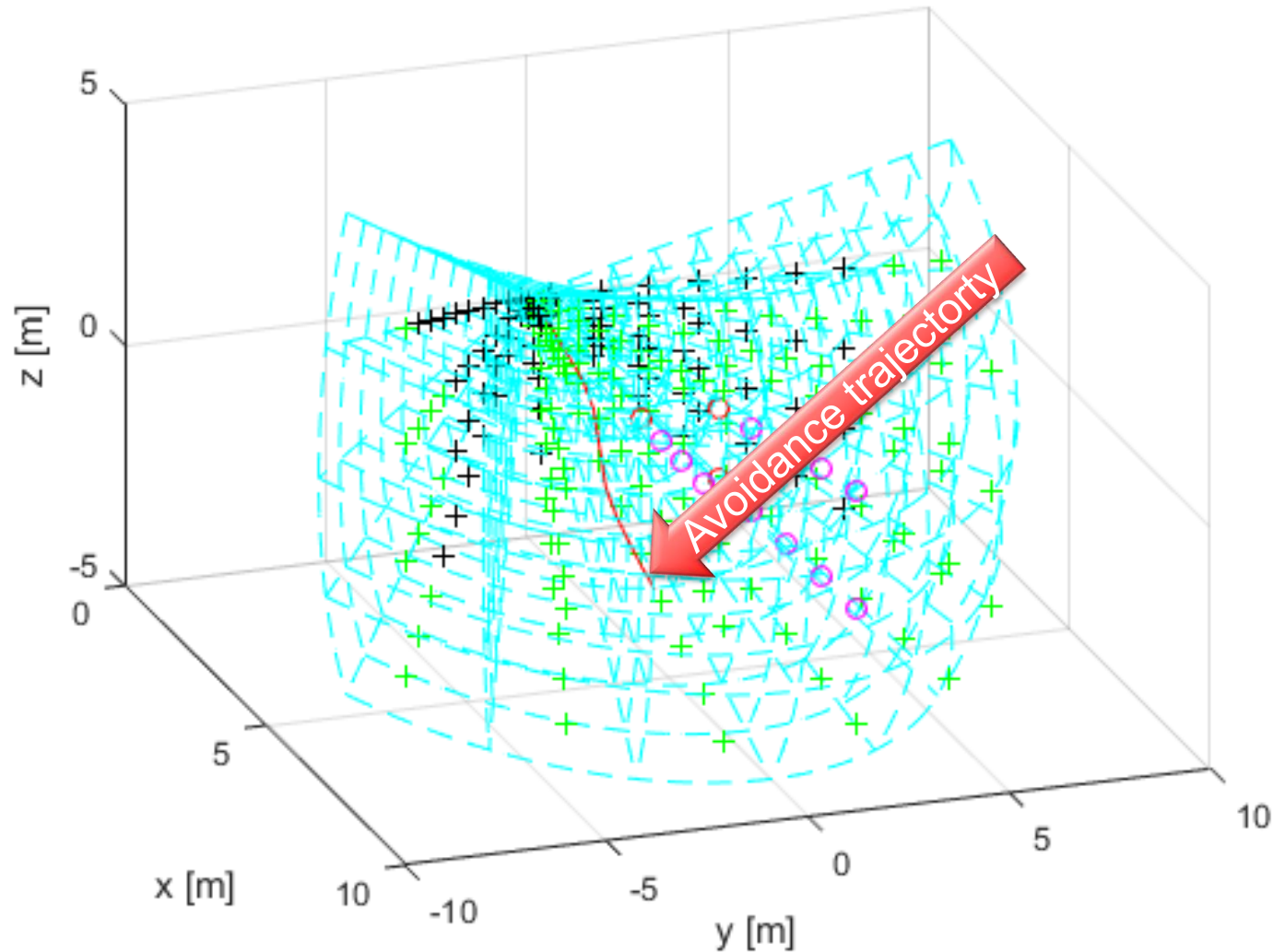




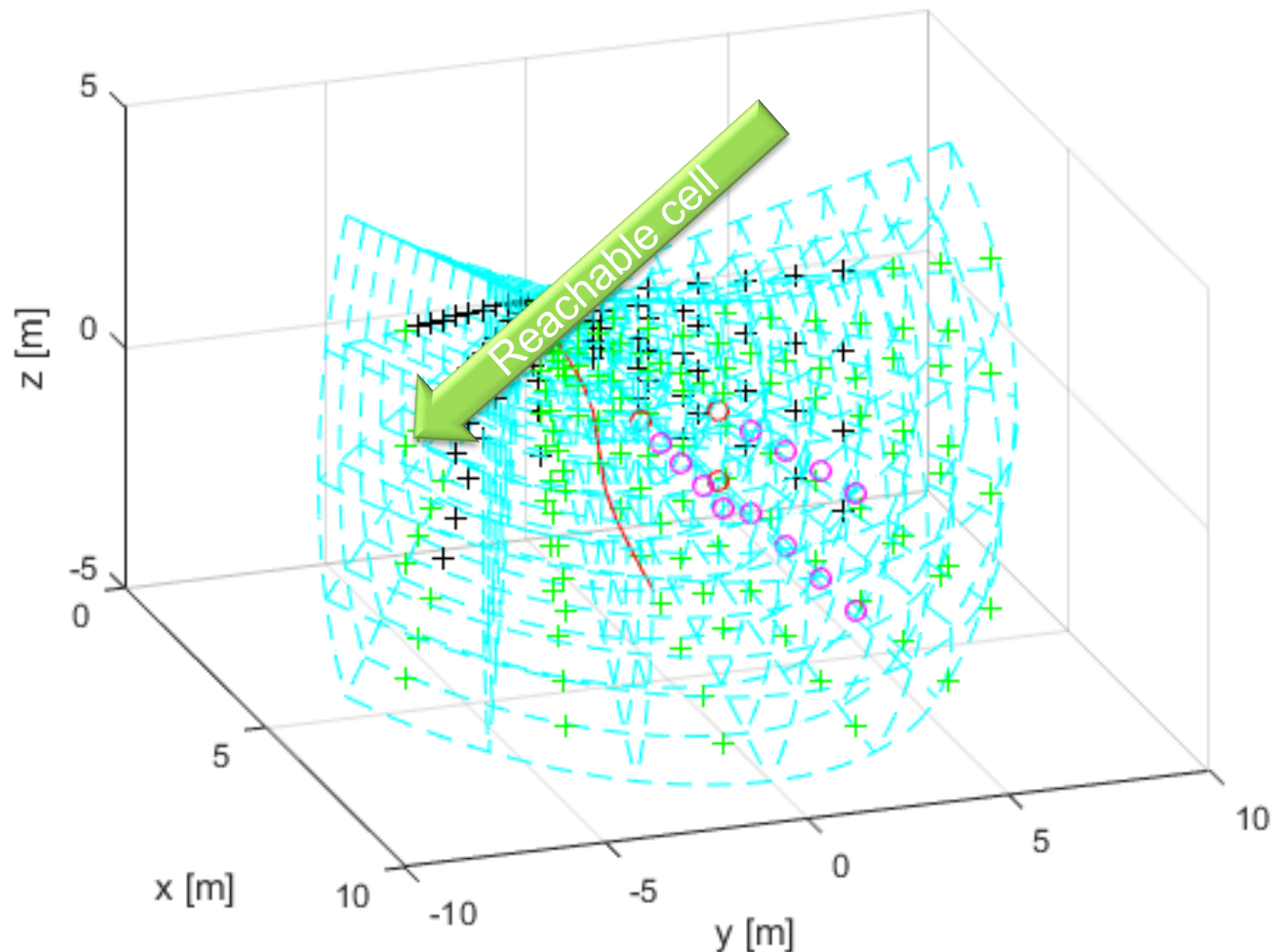
# How I represent my world



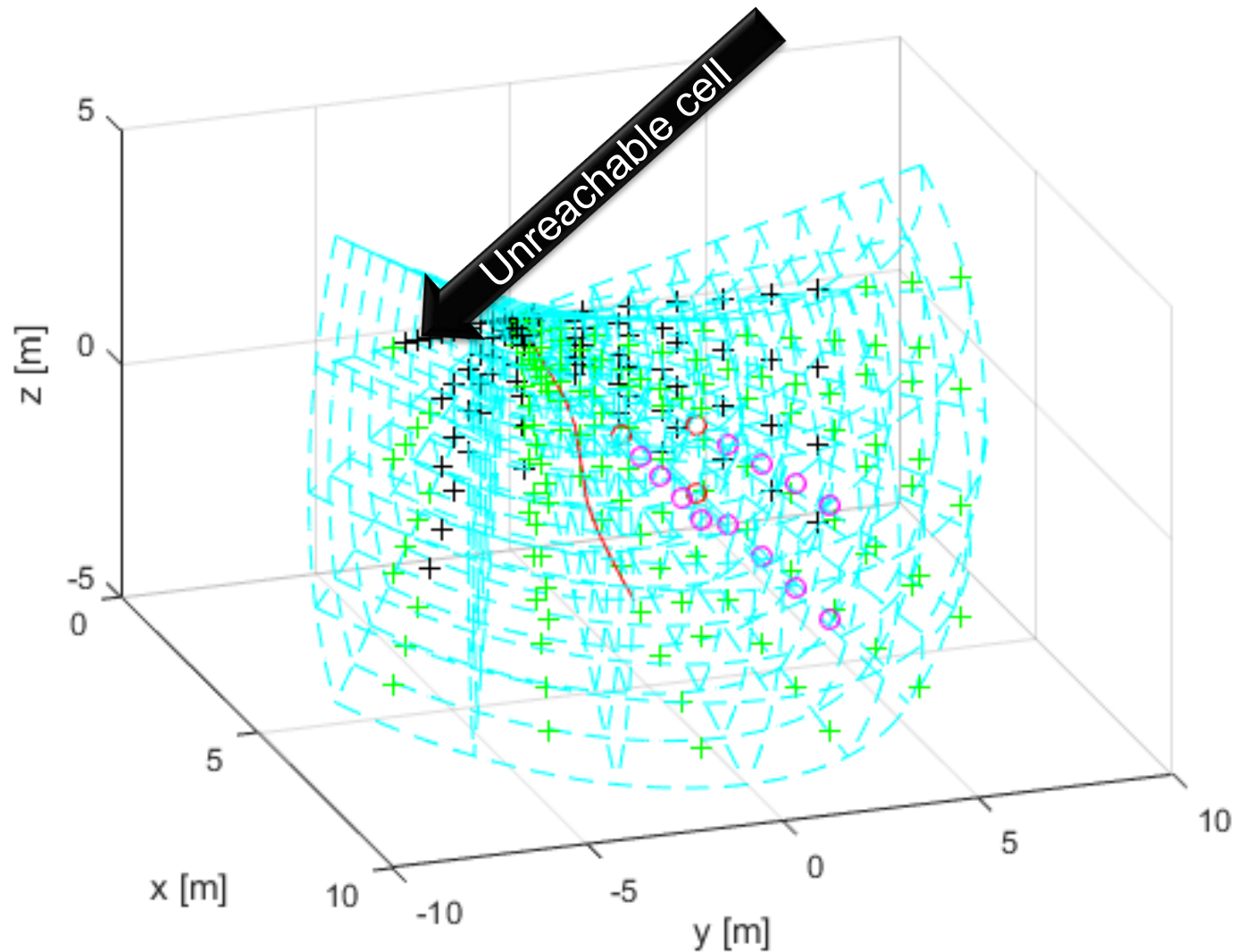
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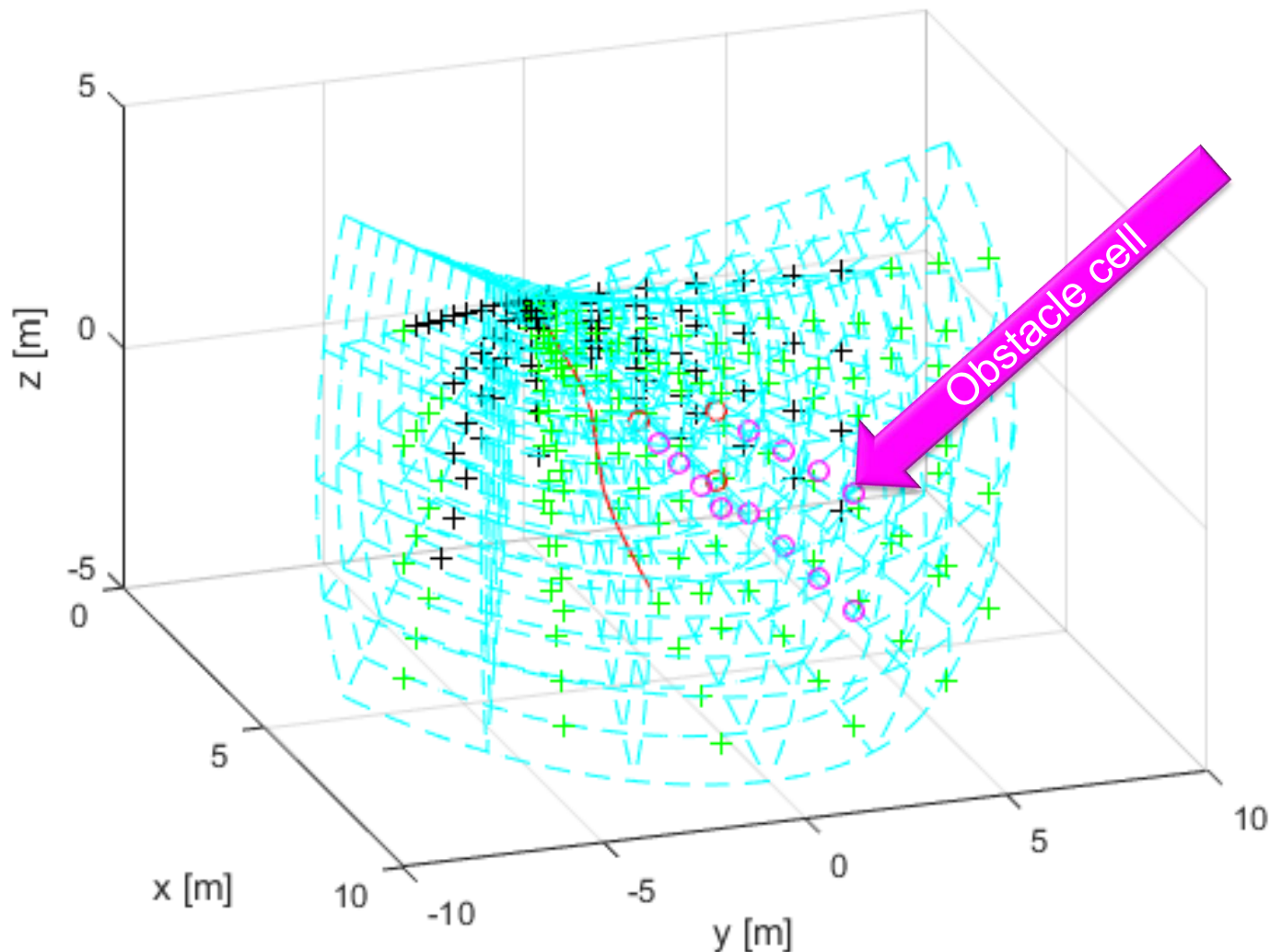
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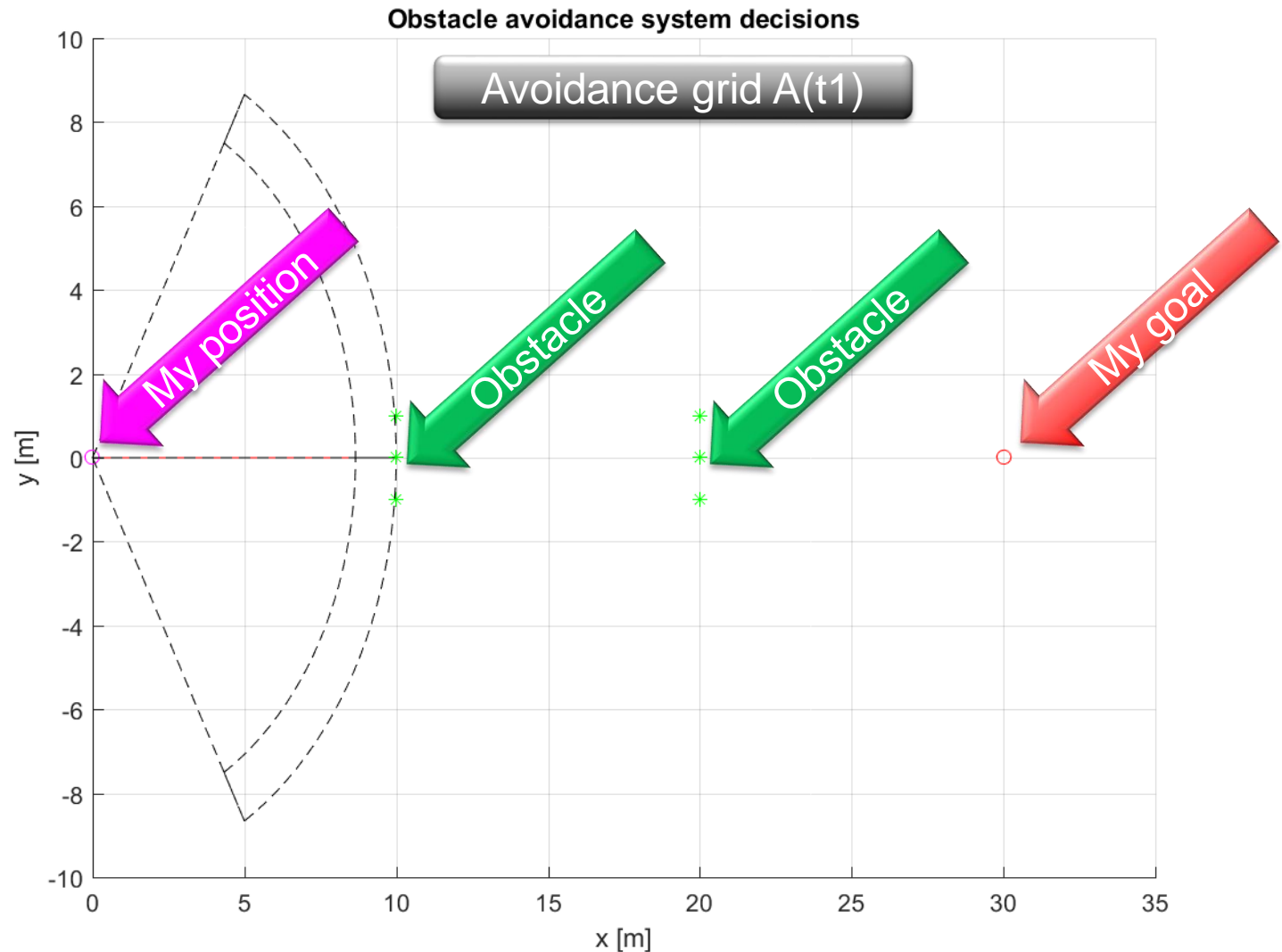


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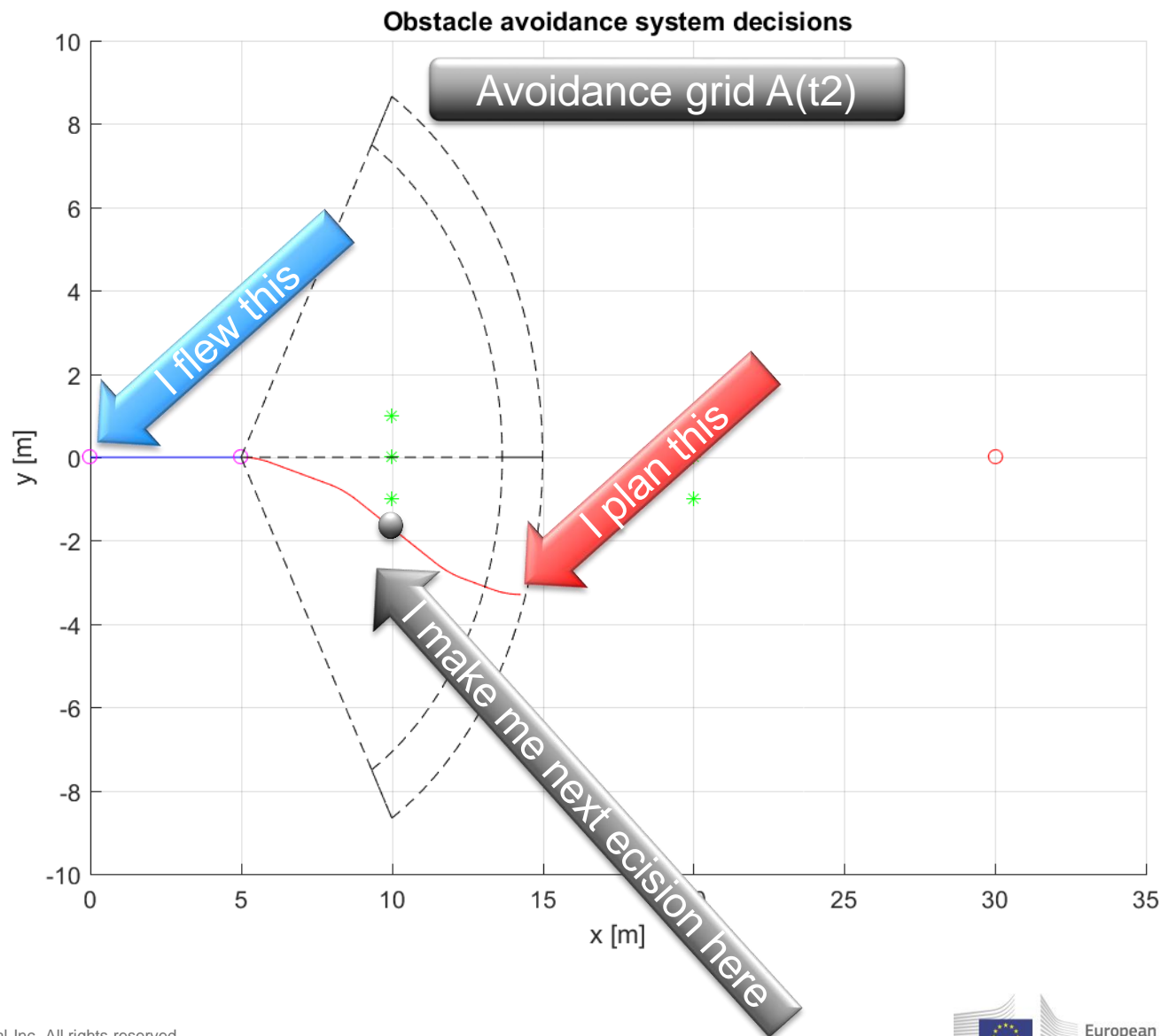




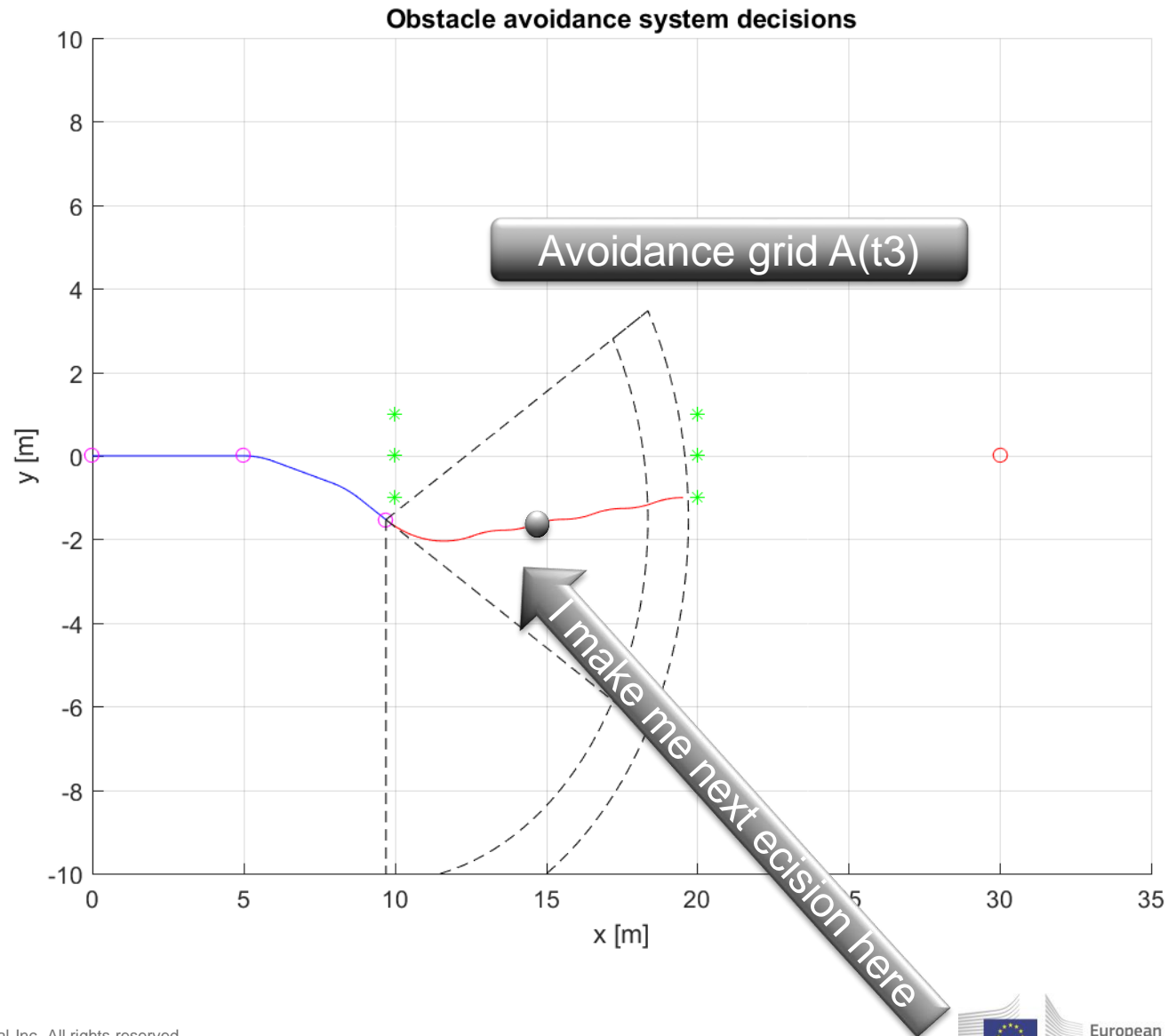
# How I join multiple avoidance grids (1)



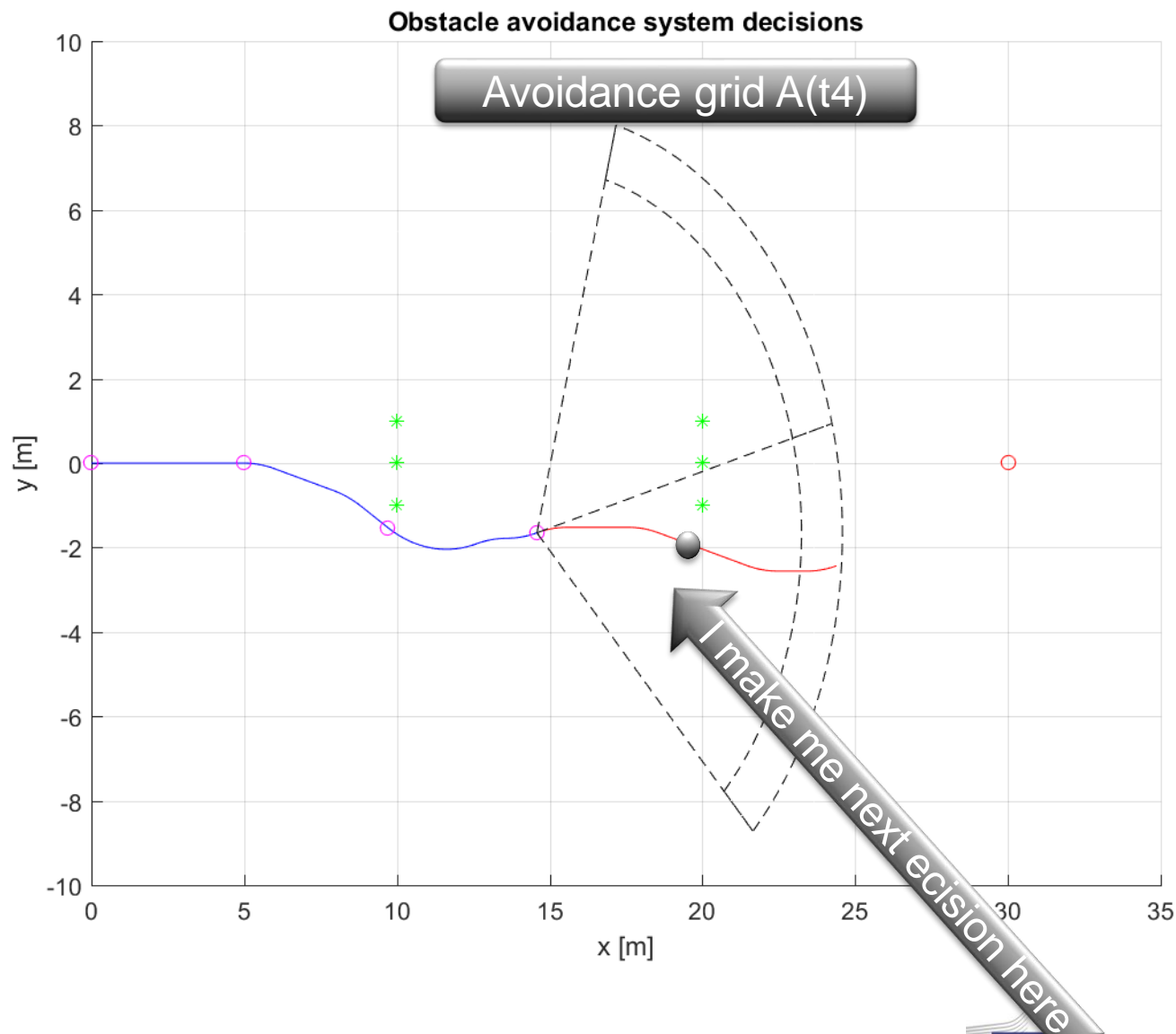
# How I join multiple avoidance grids (2)



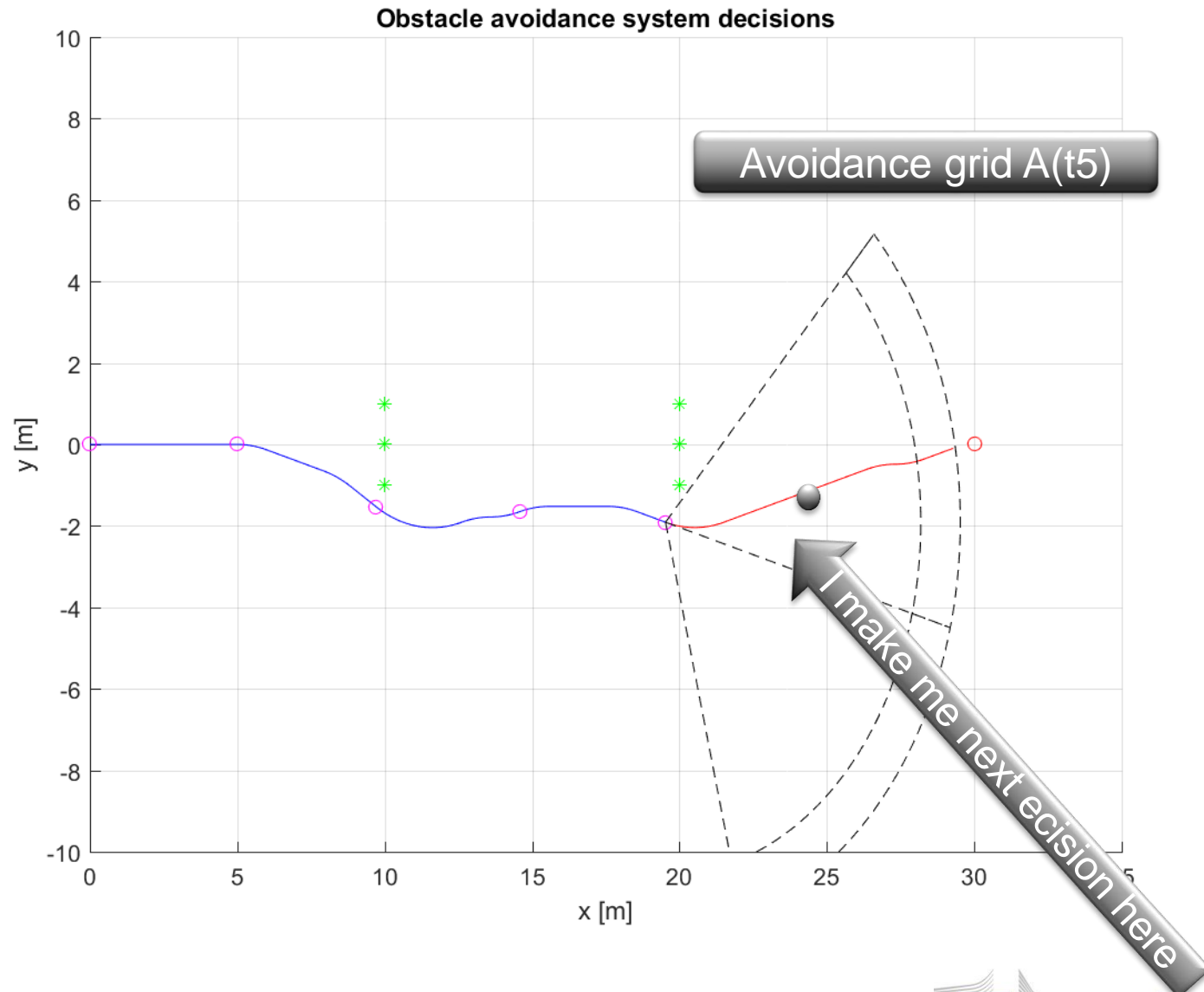
# How I join multiple avoidance grids (3)



# How I join multiple avoidance grids (4)

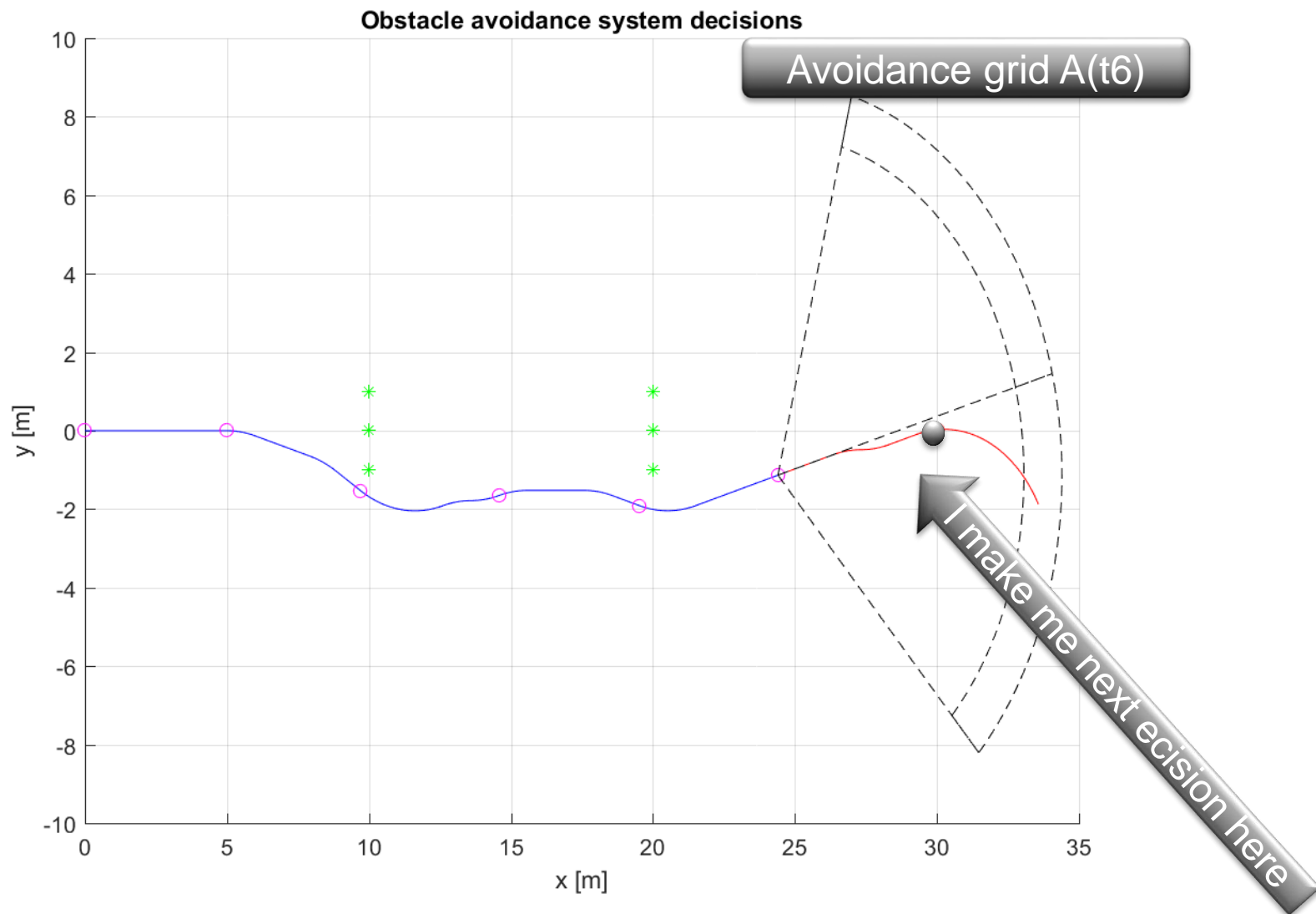


# How I join multiple avoidance grids (5)





# How I join multiple avoidance grids (6)



# How I avoided obstacles

