

Appendix B

Simplified Framework Conceptual Scheme

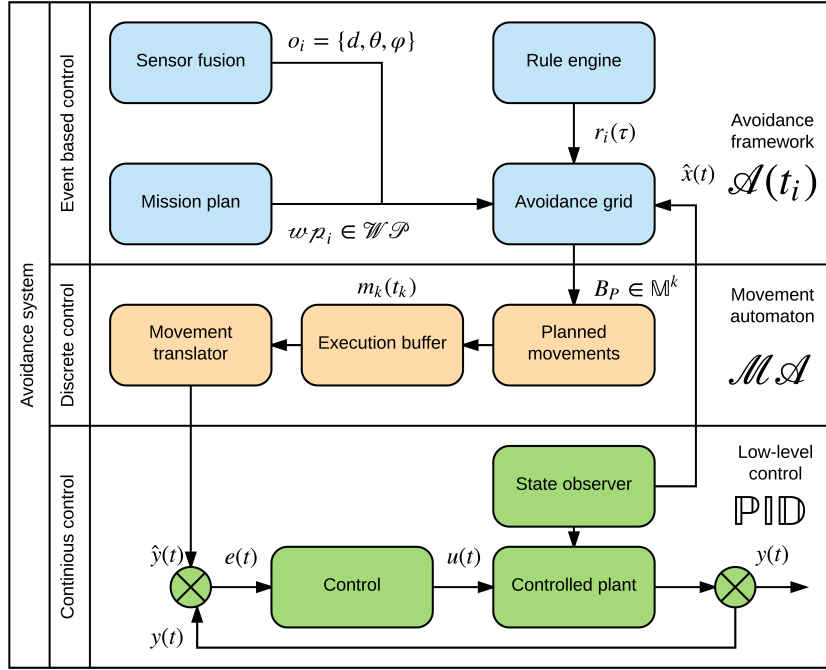


Figure B.1: Obstacle avoidance based on Reach sets concept [1].

Conceptual scheme: The overall concept of *Detect and Avoid Framework* (fig. B.1) is taking architecture from LSTS tool chain [2, 3]. The UAS part is based on *LSTS Dune* and it can be easily integrated in future.

1. *Continuous control* - is not solved in this work, its kept in scheme for reference.
2. *Discrete control* - it bridges event based *Detect and Avoid* core functionality with *Continuous control*. Its covered by *Movement Automaton* (sec. ??).
3. *Event based control* - covers major functionalists:

- a. *Sensor (Data) fusion* - the main feed of information, implementation of *sensor fusion* (sec. ??) and *data fusion* (sec. ??) contributing the avoidance events, introduced in (sec. ??).
- b. *Mission plan* - feeding actual goal and objectives to *Navigation Algorithm* (sec. ??) and obeying *UTM directives* (sec. ??).
- c. *Avoidance Grid* - using mainly *Approximation of Reachable Space* (sec. ??) in *Avoidance Maneuver Estimation*.
- d. *Rule engine* - enforcing UTM directives (sec. ??).

Surveillance Improvements in Our Work: *Hierarchical calculation* is addressed in *Mission Control run* (sec: ??) where threats are hierarchically applied based on *severity*.

Source reliability evaluation is addressed in *Static Obstacles* (sec. ??) and *Moving Obstacles* (??). The main rating for *Detected obstacle*, *Map Obstacle* and *Visibility* of space are established there.

Clear rating definition - the *Reachability* of space portion and *Safety* rating for trajectory are established in *Avoidance Grid Run* (sec. ??)

Reach Set Improvements in Our Work: *Limited system dimension* - the discretization due the higher system dimension and increased maneuver complexity goes hand-in-hand with *pre-calculation* of the *Reach Set*. This shortcoming is addressed in (sec. ??).

Real time optimization - replaced by *Discrete offline optimization problem*. The *general cost function* is given in (eq. ??). The optimization problem solved in this work is defined in (eq. ??).

Continuous space disparity - The *pre-calculated reach set estimation* can be valid with small *marginal error* for some region in *system state space*. The dynamic method for state space segmentation can be used [4]. This aspect is not addressed in this work, because it is strongly depending on the system behind movement automaton.

Trajectory Tracking - The *movement automaton* (def. ??) in Control Mode can be used to track reference trajectory in form of *Movement Buffer*(def. ??). Other option is to use *thick waypoint trajectory tracking for UAS* like in [5] or [6]. The work will use only *Movement Automaton* as controller/predictor.

Bibliography

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