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# Rhino search challenge

Kenyatta University, 21.01.2025



# Background

- Ol Pejeta is home to the last two remaining northern white rhinos, and a sanctuary for over 165 critically endangered black rhinos.
- The black rhinos need to be seen every 3 days.
- If that's not the case, search parties are sent out in the parc until they find the missing rhino.
- Drones might be able to help this effort!



# Rhino search challenge

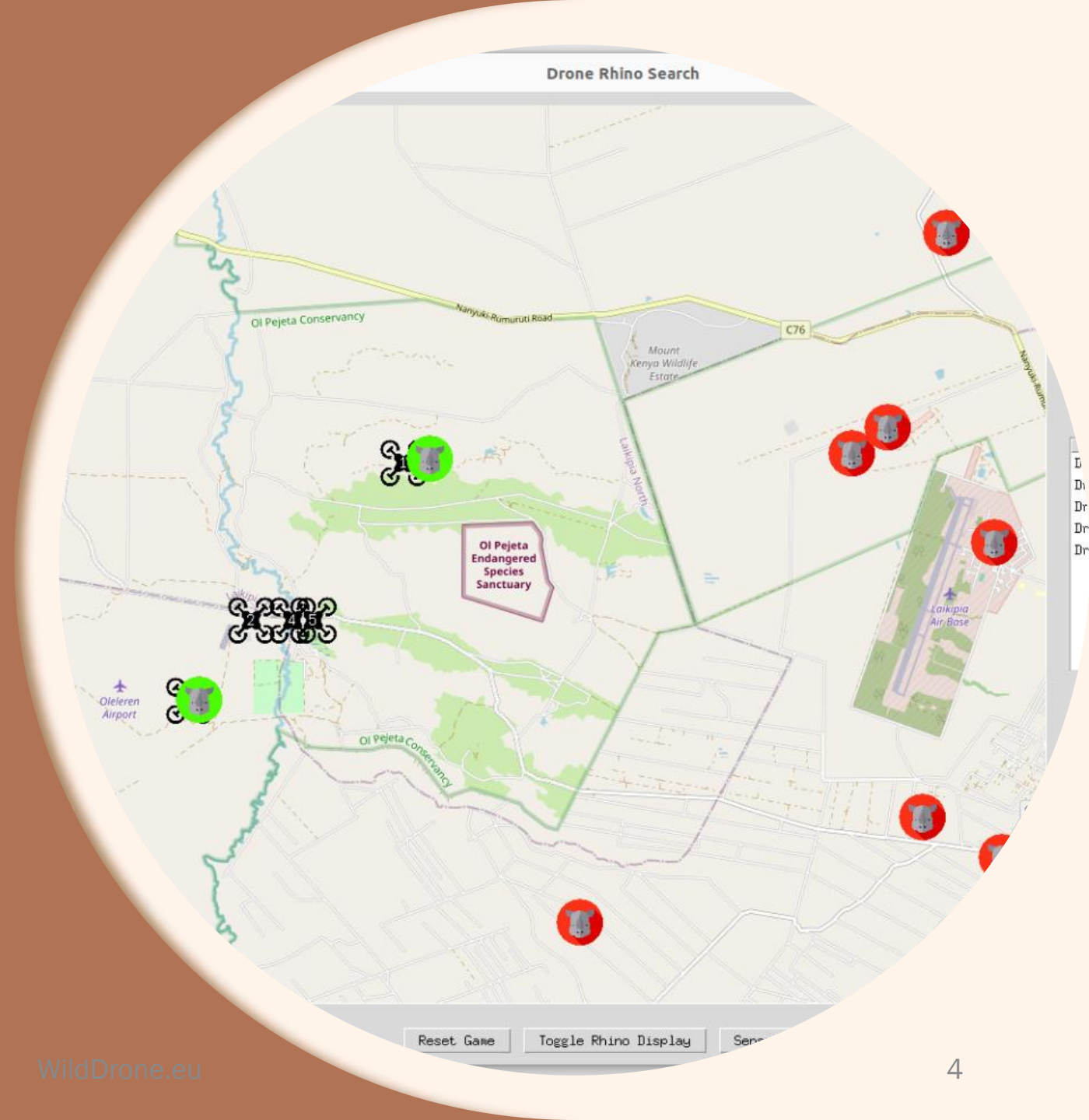
- Each team gets to control a drone in Ol Pejeta
- The drone is equipped with a **rhino range sensor** and a **downward-facing camera**
  - The range sensor has a detection range of **200m**.
  - The camera has a field of view of **50m** on the ground.
- Your goal is to find a strategy to find and take a picture of all the rhinos in the park.





# Practicals

- Remote simulated drones
- Try different search strategies
- Software with holes to fill





# Download today's scripts

meierkilian / ArdupilotIntro <https://github.com/meierkilian/ArdupilotIntro>

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SE-Reid Added Plane Param File

Practicals	Added pres
Presentations	Added pres
.gitattributes	Initial commit
.gitignore	Initial commit
plane.parm	Added Plane Param

Clone

HTTPS SSH GitHub CLI

<https://github.com/meierkilian/ArdupilotIntro.git>

Clone using the web URL.

Open with GitHub Desktop

Download ZIP

Extract it!

5



# Installing python packages

- Packages
  - Open terminal (WIN+R, then type “cmd” and press Enter)
  - pip install numpy
  - pip install dronekit
  - pip install pymap3d
- Run helloworld.py
  - Change directory to the folder “Practicals/RhinoChallenge”
  - python helloworld.py
- Open “rhinoChallengeTasks.py” in your favourite text/code editor

# TASK 1: is a waypoint reached?



- How can we check if a waypoint is reached?

# TASK 2: wait until a waypoint reached?



- How can we send a drone to a waypoint and then wait until it reached it?





# TASK 3: Connect to the drone

- Connect to local network
  - SSID: ANVLAN729
  - Password: ministrylevel369
- Fill in the system ID of your group
  - See the screen for your group IP address and port

# TASK 4: run the manual search



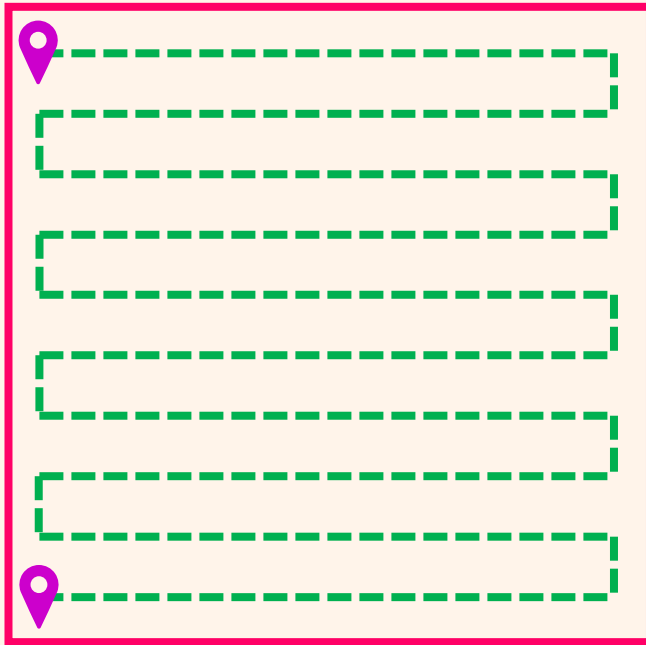
- Can you find any rhino?
- Is it a convenient way of searching?

# TASK 4: run the manual search

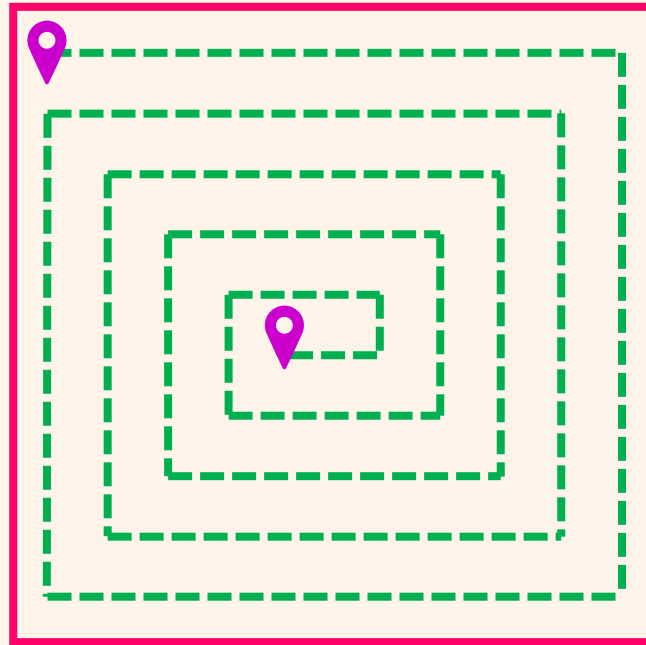


- Can you find any rhino?
- Is it a convenient way of searching?

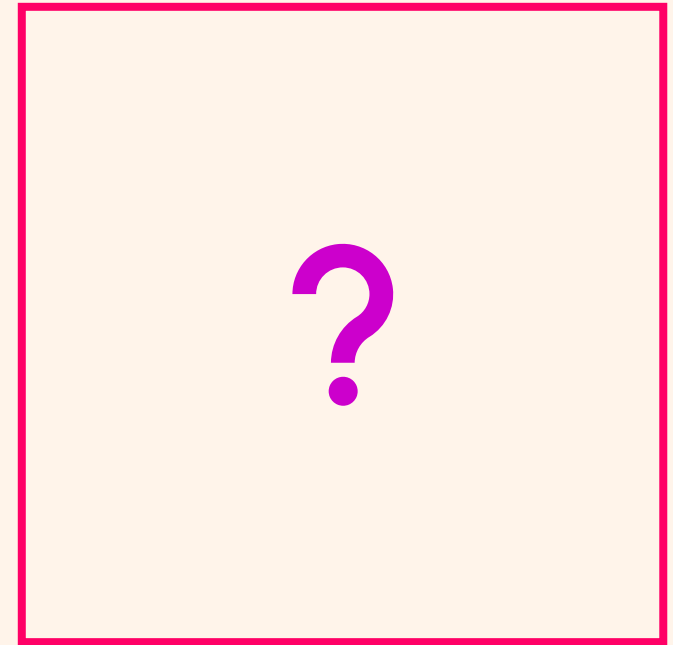
# TASK 5: Search Patterns



Lawnmower



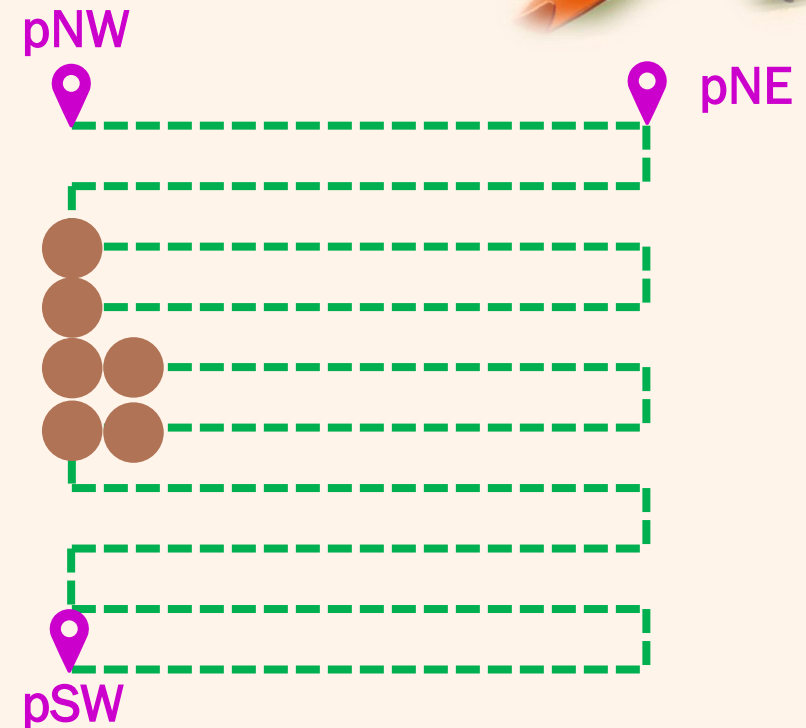
Spiral





# TASK 5: lawnmower pattern

- Explain what those 4 lines do.
  - What are pNW, pNE and PSW?
  - Why divided by sensorRange?
  - What about  $2^{**}0.5$ ?
  - Why +1?
  - What does the linspace() function do?



```
# @@@ TASK 5 @@@: Explain what the next 4 lines do.  
latStepNbr = int(pNW.distTo(pNE) // (PARAM.foundThreshold / 2**0.5) + 1)  
lonStepNbr = int(pNW.distTo(pSW) // (PARAM.foundThreshold / 2**0.5) + 1)  
lat_points = np.linspace(PARAM.limit_south, PARAM.limit_north, latStepNbr).tolist()  
lon_points = np.linspace(PARAM.limit west, PARAM.limit east, lonStepNbr).tolist()
```



# TASK 6: run the lawnmower search

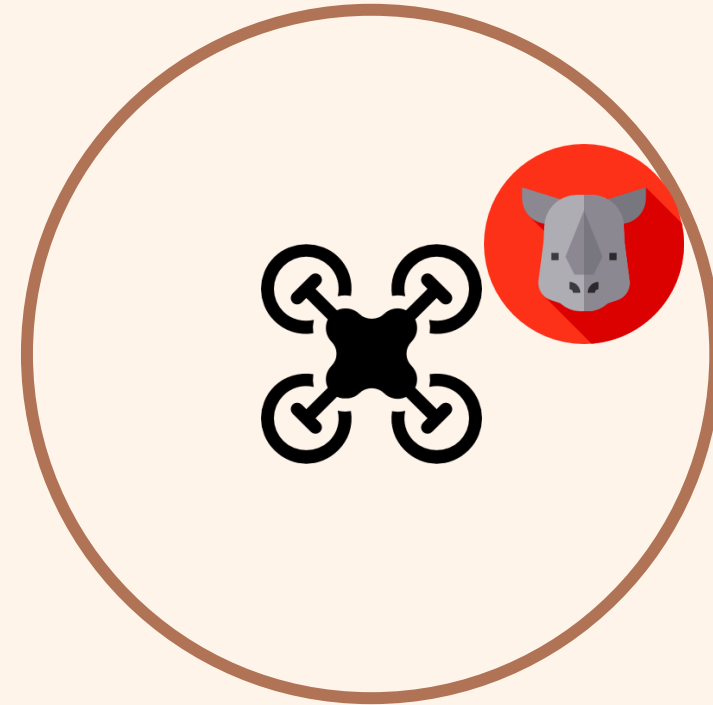
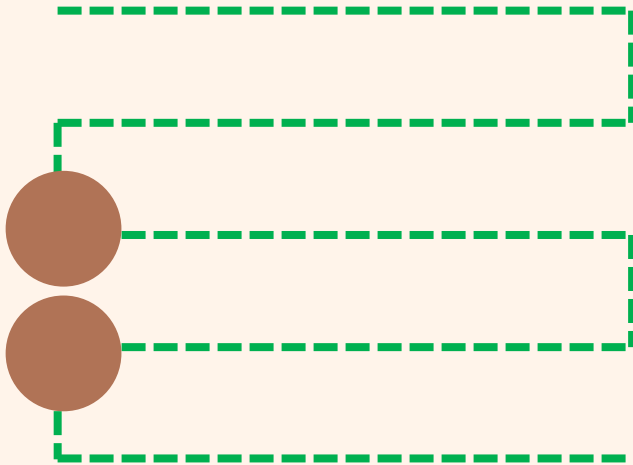
- Can you find any rhino?
- Is it more efficient than manual search?
- What is the drawback of this search?



# TASK 7: triangulation

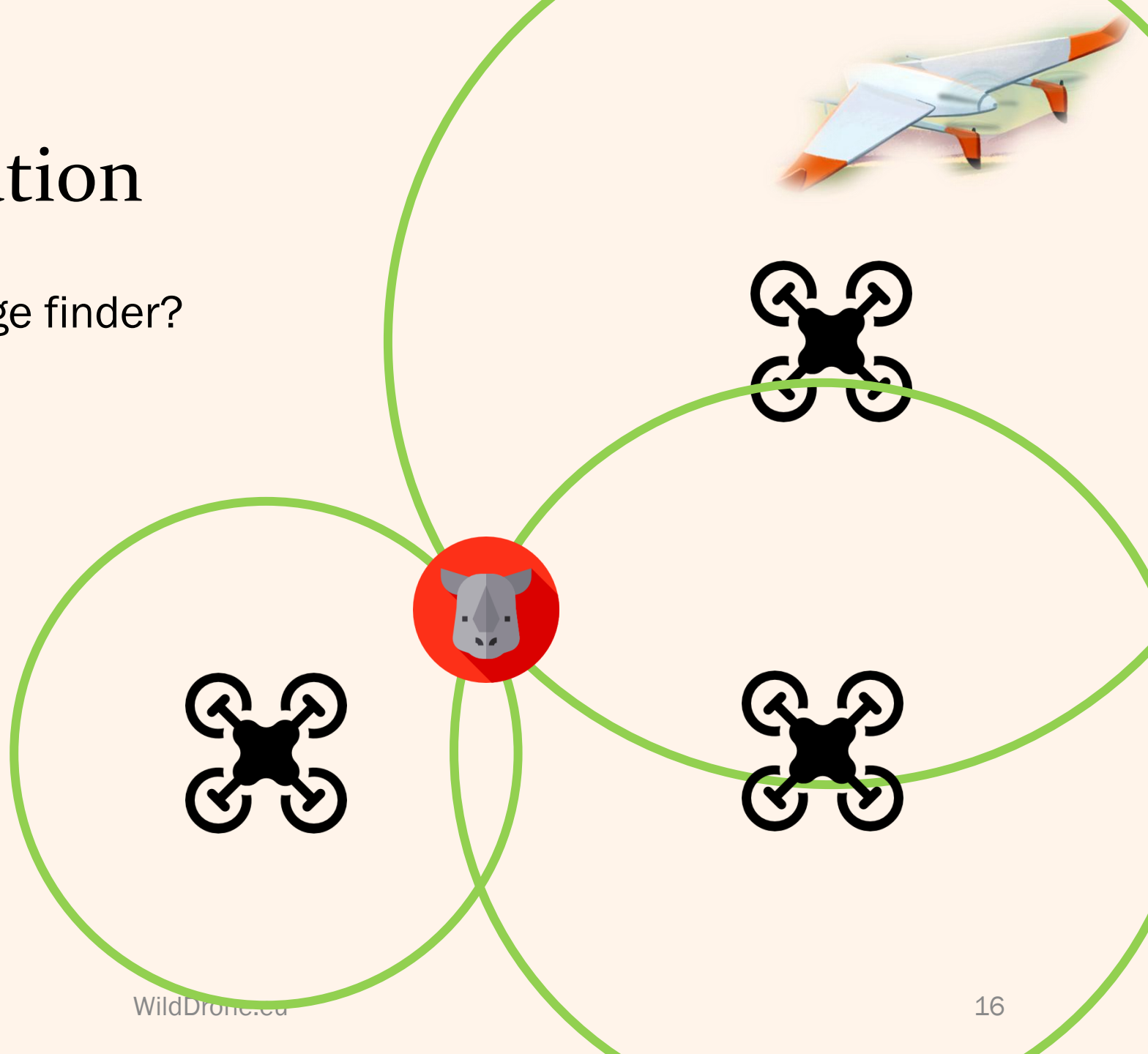


- How should we use the range finder?



# TASK 7: triangulation

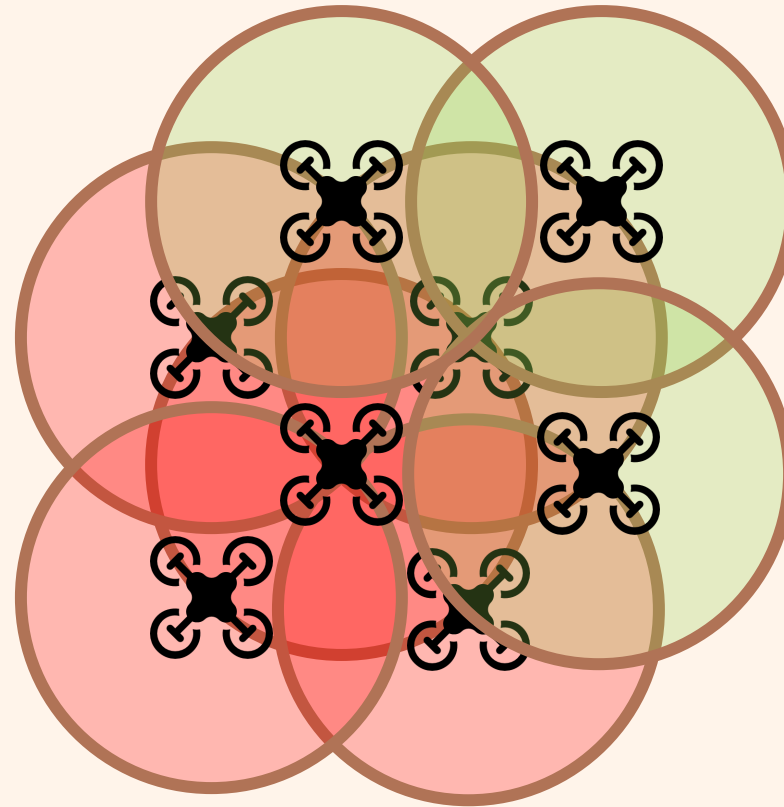
- How should we use the range finder?



# TASK 7: triangulation



- How should we use the range finder?





# TASK 8: run the triangulation search

- Can you find any rhino?
- Is it more efficient than the lawnmower search?
- Do you think a rhino ranger finder is something we can build?

# Conclusion

Give an overview of how to design and conduct a safe semi-autonomous drone (quadcopter) operation in the context of wildlife conservation.

- Autopilot software and simulation (Ardupilot)
- Ground Control Station software (Mission planner)
- Communication protocol (Mavlink)
- Safe operation (SORA)
- Practical work





Engineering and  
Physical Sciences  
Research Council



Funded by  
the European Union

**Project funded by**



Schweizerische Eidgenossenschaft  
Confédération suisse  
Confederazione Svizzera  
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Swiss Confederation

Federal Department of Economic Affairs,  
Education and Research EAER  
**State Secretariat for Education,  
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*WildDrone is an MSCA Doctoral Network funded by the European Union's Horizon Europe research and innovation funding programme under the Marie Skłodowska-Curie grant agreement no. 101071224. Views and opinions expressed are those of the author(s) only and do not necessarily reflect those of the European Union or the European Research Executive Agency. Neither the European Union nor the granting authority can be held responsible for them.*





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