

Precision Control of an Autonomous Surface Vessel



Alejandro Alonso García, Anders Egelund Kjeldal, Himal Kooverjee,
Niels Skov Vestergaard, Noelia Villamarzo Arruñada

Agenda



- ▶ Introduction
 - Use Case
- ▶ System Description
- ▶ Model
 - Reference Frames
 - Model Equations
 - Model Verification
- ▶ Control Approach
- ▶ Sensor Fusion
- ▶ Inner Controller
- ▶ Outer Controller
- ▶ Results
- ▶ Conclusion

Introduction

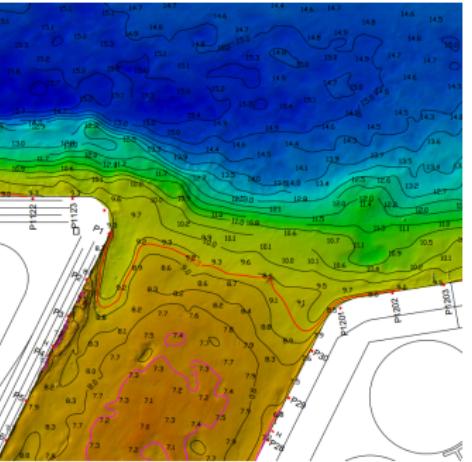


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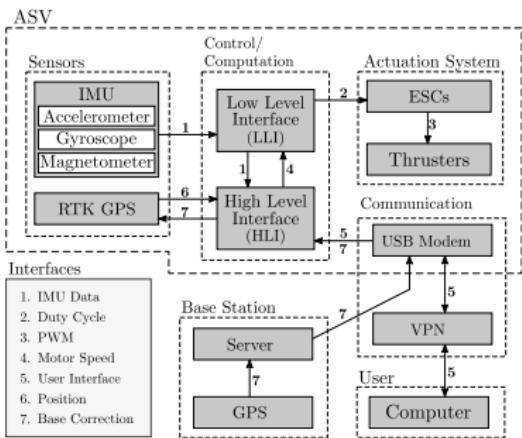
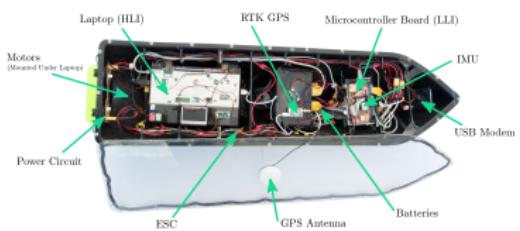


Introduction

Use Case



System Description

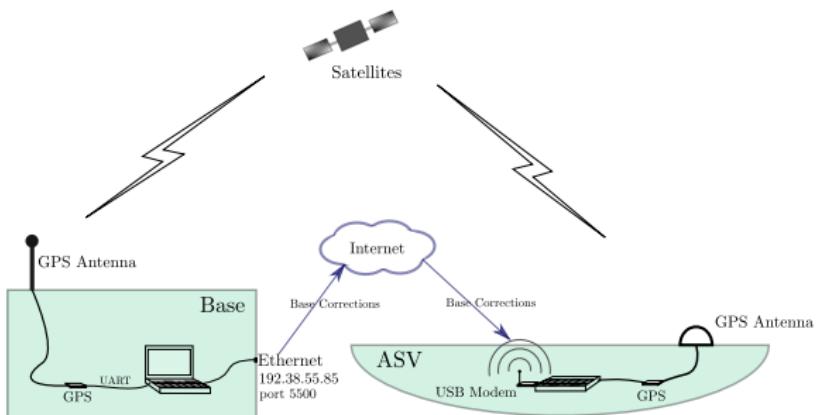


System Description

RTK GPS

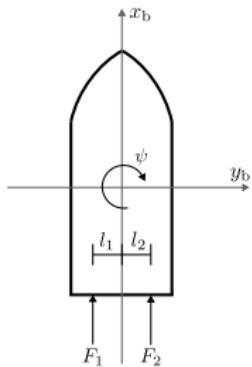
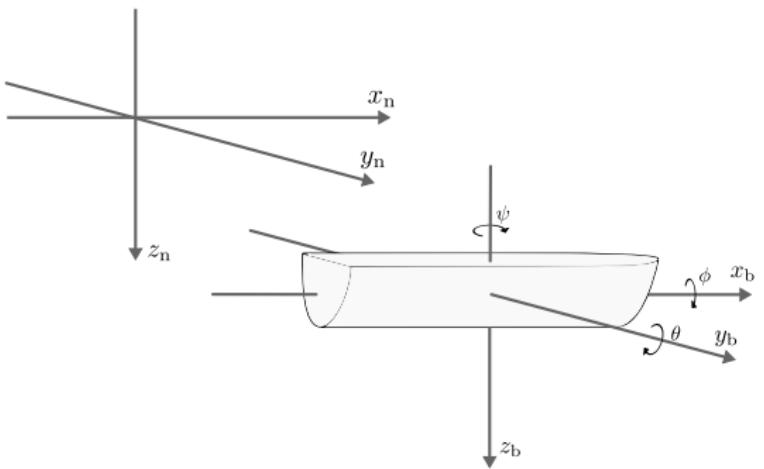


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Model

Reference Frames



Model

Model Equations



$$m\ddot{x}_b = F_1 + F_2 - d_{\dot{x}_b} \dot{x}_b + F_{x_b}$$

$$m\ddot{y}_b = -d_{\dot{y}_b} \dot{y}_b + F_{y_b}$$

$$m\ddot{z}_b = -d_{\dot{z}_b} \dot{z}_b + F_{z_b}$$

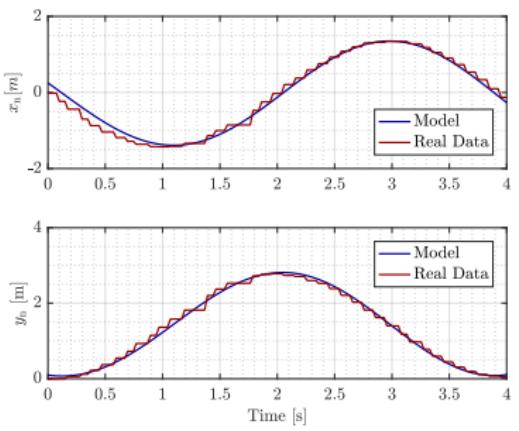
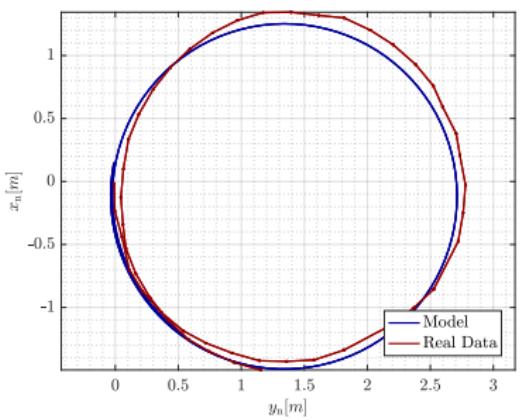
$$I_x \ddot{\phi} = -d_{\dot{\phi}} \dot{\phi} + T_\phi$$

$$I_y \ddot{\theta} = -d_{\dot{\theta}} \dot{\theta} + T_\theta$$

$$I_z \ddot{\psi} = F_1 I_1 - F_2 I_2 - d_{\dot{\psi}} \dot{\psi}$$

Model

Model Verification

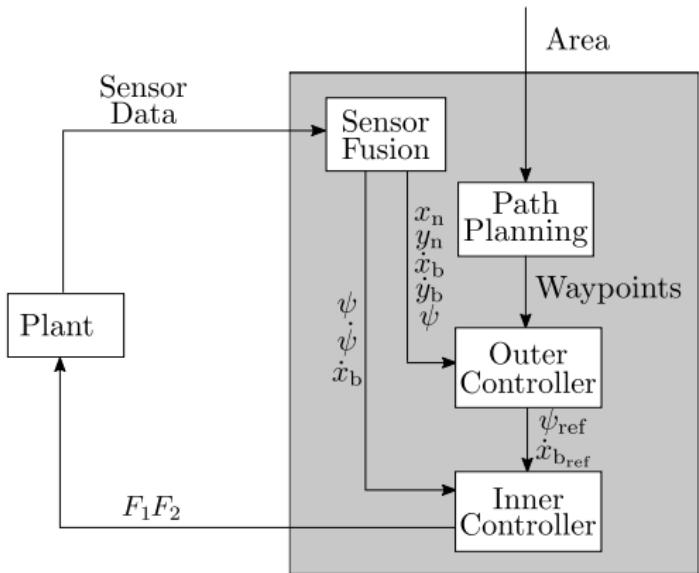


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- ▶ Introduction
- ▶ System Description
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- ▶ **Control Approach**
- ▶ **Sensor Fusion**
 - Attitude Kalman Filter
 - Position Kalman Filter
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- ▶ Outer Controller
- ▶ Results
- ▶ Conclusion

Control Approach



Sensor Fusion

Kalman Filter Structure



Sensor Fusion

Attitude Kalman Filter



$$\hat{\mathbf{x}}_{\text{att}}(k+1) = \mathbf{A}_{\text{att}} \hat{\mathbf{x}}_{\text{att}}(k) + \mathbf{B}_{\text{att}} \mathbf{u}(k) + \mathbf{w}_{\text{att}}(k)$$

$$\mathbf{y}_{\text{att}}(k) = \mathbf{C}_{\text{att}} \hat{\mathbf{x}}_{\text{att}}(k) + \mathbf{v}_{\text{att}}(k)$$

$$\mathbf{Q}_{\text{att}} = \text{diag}(\sigma_{\phi}^2, \sigma_{\theta}^2, \sigma_{\psi}^2, \sigma_{\dot{\phi}}^2, \sigma_{\dot{\theta}}^2, \sigma_{\dot{\psi}}^2, \sigma_{\ddot{\phi}}^2, \sigma_{\ddot{\theta}}^2, \sigma_{\ddot{\psi}}^2)$$

$$\mathbf{R}_{\text{att}} = \text{diag}(\sigma_{\phi,\text{acc}}^2, \sigma_{\theta,\text{acc}}^2, \sigma_{\psi,\text{mag}}^2, \sigma_{\dot{\phi},\text{gyro}}^2, \sigma_{\dot{\theta},\text{gyro}}^2, \sigma_{\dot{\psi},\text{gyro}}^2)$$

$$\hat{\mathbf{x}}_{\text{att}} = [\phi \quad \theta \quad \psi \quad \dot{\phi} \quad \dot{\theta} \quad \dot{\psi} \quad \ddot{\phi} \quad \ddot{\theta} \quad \ddot{\psi}]^T$$

$$\mathbf{y}_{\text{att}} = [\phi_{\text{acc}} \quad \theta_{\text{acc}} \quad \psi_{\text{mag}} \quad \dot{\phi}_{\text{gyro}} \quad \dot{\theta}_{\text{gyro}} \quad \dot{\psi}_{\text{gyro}}]^T$$

$$\mathbf{u} = [F_1 \quad F_2]^T$$

Sensor Fusion

Attitude Kalman Filter



$$\mathbf{A}_{\text{att}} = \begin{bmatrix} 1 & 0 & 0 & T_s & 0 & 0 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 & T_s & 0 & 0 & 0 & 0 \\ 0 & 0 & 1 & 0 & 0 & T_s & 0 & 0 & 0 \\ 0 & 0 & 0 & 1 & 0 & 0 & T_s & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 & 0 & T_s & 0 \\ 0 & 0 & 0 & 0 & 0 & 1 & 0 & 0 & T_s \\ 0 & 0 & 0 & 0 & 0 & 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & -\frac{d_\phi}{I_x} & 0 & 0 & -T_s \frac{d_\phi}{I_x} & 0 & 0 \\ 0 & 0 & 0 & 0 & -\frac{d_\theta}{I_y} & 0 & 0 & -T_s \frac{d_\theta}{I_y} & 0 \\ 0 & 0 & 0 & 0 & 0 & -\frac{d_\psi}{I_z} & 0 & 0 & -T_s \frac{d_\psi}{I_z} \end{bmatrix}$$

$$\mathbf{B} = \begin{bmatrix} 0 & 0 \\ 0 & 0 \\ 0 & 0 \\ 0 & 0 \\ 0 & 0 \end{bmatrix} \quad \mathbf{C} = \begin{bmatrix} 1 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 1 & 0 & 0 & 0 & 0 & 0 & 0 \end{bmatrix}$$

Sensor Fusion

Attitude Kalman Filter



$$\hat{\mathbf{x}}_{\text{att}}(k+1|k) = \mathbf{A}_{\text{att}} \hat{\mathbf{x}}_{\text{att}}(k|k) + \mathbf{B}_{\text{att}} \mathbf{u}(k)$$

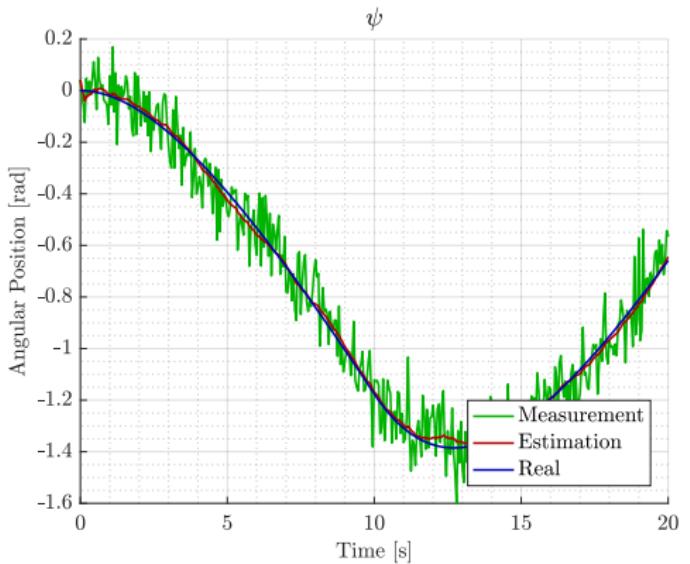
$$\mathbf{P}_{\text{att}}(k+1|k) = \mathbf{A}_{\text{att}} \mathbf{P}_{\text{att}}(k|k) \mathbf{A}_{\text{att}}^T + \mathbf{Q}_{\text{att}}$$

$$\hat{\mathbf{x}}_{\text{att}}(k+1|k+1) = \hat{\mathbf{x}}_{\text{att}}(k+1|k) + \mathbf{K}(k+1) [\mathbf{y}_{\text{att}}(k+1) - \mathbf{C}_{\text{att}} \hat{\mathbf{x}}_{\text{att}}(k+1|k)]$$

$$\mathbf{P}_{\text{att}}(k+1|k+1) = \left[\mathbf{I} - \mathbf{K}(k+1) \mathbf{C}_{\text{att}}^T \right] \mathbf{P}_{\text{att}}(k+1|k)$$

Sensor Fusion

Attitude Kalman Filter



Sensor Fusion

Position Kalman Filter



$$\begin{aligned}\hat{\mathbf{x}}_{\text{pos}}(k+1) &= \mathbf{A}_{\text{pos}}(k)\mathbf{x}_{\text{pos}}(k) + \mathbf{B}_{\text{pos}}\mathbf{u}(k) + \mathbf{w}_{\text{pos}}(k) \\ \mathbf{y}_{\text{pos}}(k) &= \mathbf{C}_{\text{pos}}\hat{\mathbf{x}}_{\text{pos}}(k) + \mathbf{v}_{\text{pos}}(k)\end{aligned}$$

$$\begin{aligned}\mathbf{Q}_{\text{pos}} &= \text{diag}(\sigma_{x_n}^2, \sigma_{y_n}^2, \sigma_{x_b}^2, \sigma_{y_b}^2, \sigma_{\ddot{x}_b}^2, \sigma_{\ddot{y}_b}^2) \\ \mathbf{R}_{\text{pos}} &= \text{diag}(\sigma_{x_{n,\text{GPS}}}^2, \sigma_{y_{n,\text{GPS}}}^2, \sigma_{\ddot{x}_{b,\text{acc}}}^2, \sigma_{\ddot{y}_{b,\text{acc}}}^2)\end{aligned}$$

$$\hat{\mathbf{x}}_{\text{pos}} = [x_n \quad y_n \quad \dot{x}_b \quad \dot{y}_b \quad \ddot{x}_b \quad \ddot{y}_b]^T$$

$$\mathbf{y}_{\text{pos}} = [x_{n,\text{GPS}} \quad y_{n,\text{GPS}} \quad \ddot{x}_{b,\text{acc}} \quad \ddot{y}_{b,\text{acc}}]^T$$

$$\mathbf{u} = [F_1 \quad F_2]^T$$

Sensor Fusion

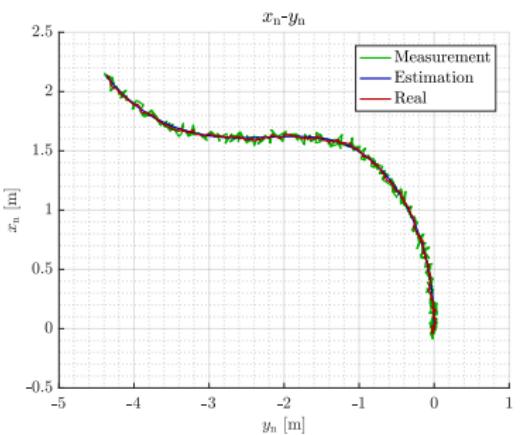
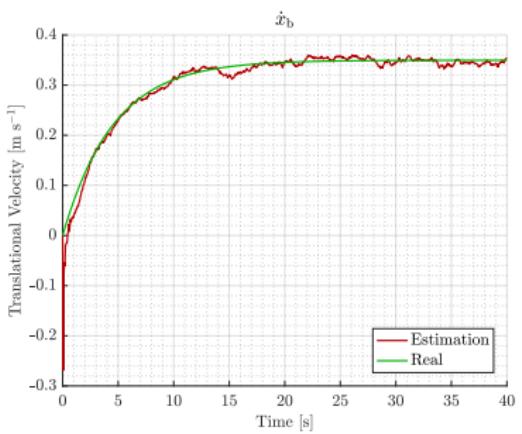
Position Kalman Filter



$$\mathbf{A}_{\text{pos}}(\phi(k), \theta(k), \psi(k)) = \begin{bmatrix} 1 & 0 & T_s \mathbf{R}_b^n(1,1) & T_s \mathbf{R}_b^n(1,2) & 0 & 0 \\ 0 & 1 & T_s \mathbf{R}_b^n(2,1) & T_s \mathbf{R}_b^n(2,2) & 0 & 0 \\ 0 & 0 & 1 & 0 & T_s & 0 \\ 0 & 0 & 0 & 1 & 0 & T_s \\ 0 & 0 & -\frac{d_x}{m} & 0 & -T_s \frac{d_x}{m} & 0 \\ 0 & 0 & 0 & -\frac{d_y}{m} & 0 & -T_s \frac{d_y}{m} \end{bmatrix}$$

Sensor Fusion

Position Kalman Filter



Agenda



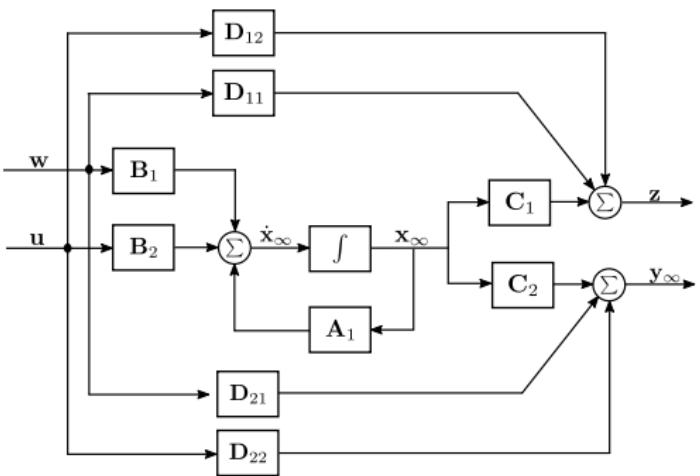
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- ▶ Model
- ▶ Control Approach
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- ▶ **Inner Controller**
 - **Robust Controller Design**
 - Linear Quadratic Regulator Design
 - Comparison of the Controllers
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- ▶ Conclusion

Inner Controller



Inner Controller

Robust Controller Design



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- ▶ Introduction
- ▶ System Description
- ▶ Model
- ▶ Control Approach
- ▶ Sensor Fusion
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 - **Controllers Comparison**
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- ▶ Results
- ▶ Conclusion

Inner Controller

Linear Quadratic Controller Design



Inner Controller

Comparison of the Controllers



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- ▶ Introduction
- ▶ System Description
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- ▶ Outer Controller
 - Path Generation Algorithm
 - Path Following Algorithm
- ▶ Results
 - Simulation Results
 - Implementation Results
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Outer Controller



Outer Controller

Path Generation Algorithm



Outer Controller

Path Following Algorithm



Results

Simulation Results



Results

Implementation Results



Conclusion



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AALBORG UNIVERSITY
DENMARK