

Precision Control of an Autonomous Surface Vessel



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Agenda



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

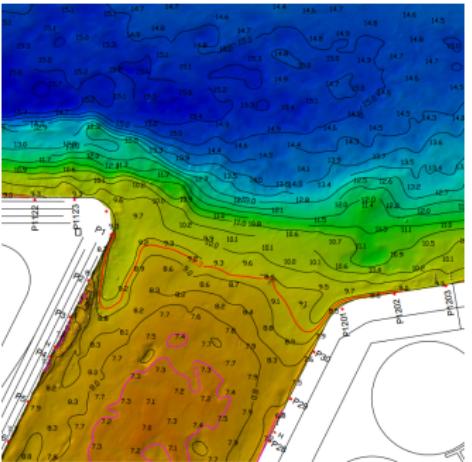
Introduction



- ▶ Applications of an Autonomous Surface Vessel (ASV)
- ▶ Bathymetric Measurements
- ▶ Control of an ASV

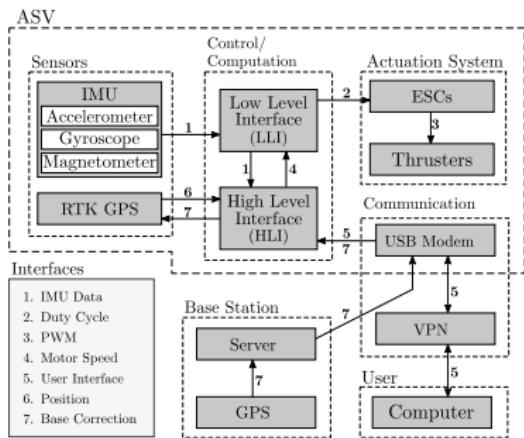
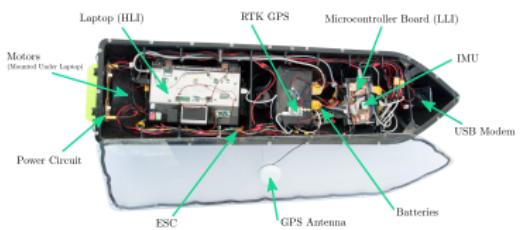
Introduction

Use Case



- ▶ Depth map used by Port of Aalborg
 - ▶ Problem: No recent knowledge of depths of the port
 - ▶ Solution: Automate smaller unmanned vessel

System Description

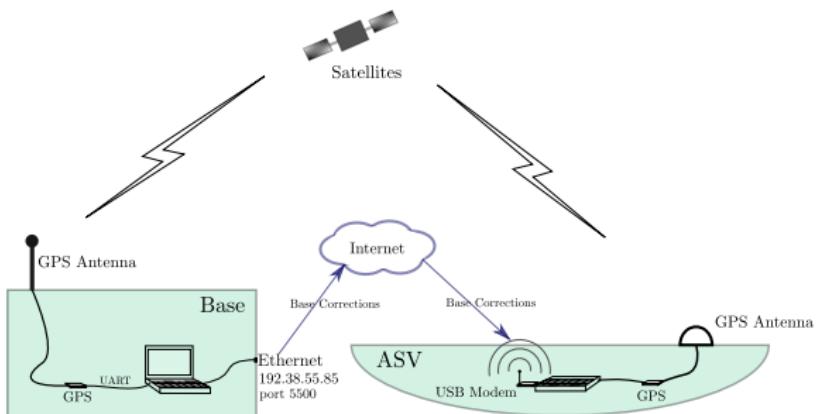


System Description

RTK GPS

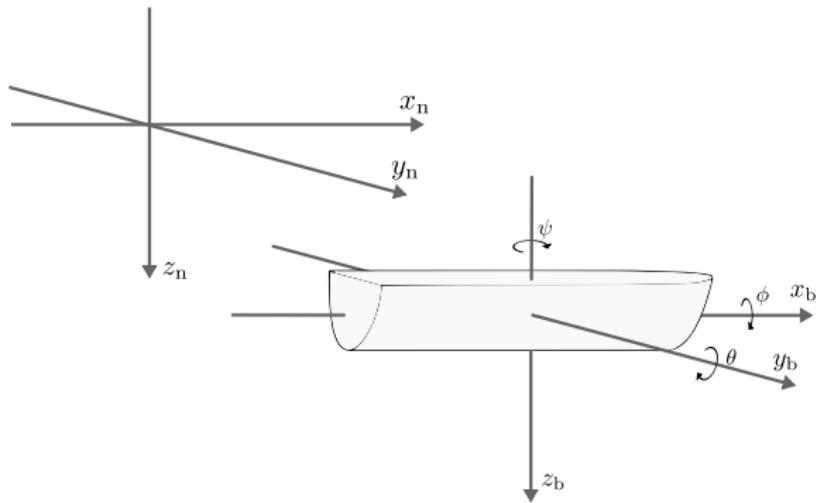


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Model

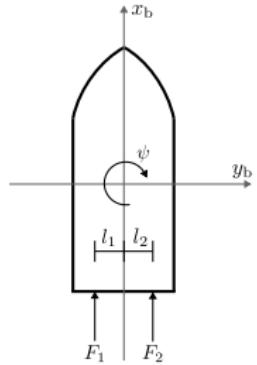
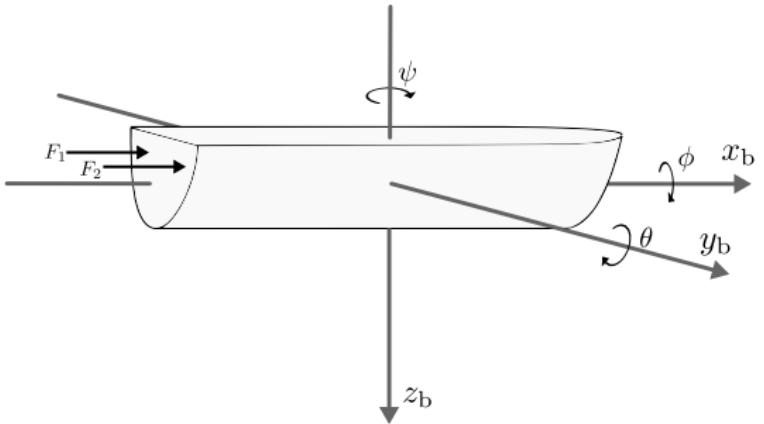
Reference Frames



- ▶ Inertial Frame
- ▶ Body Frame

Model

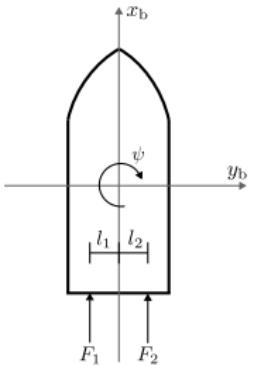
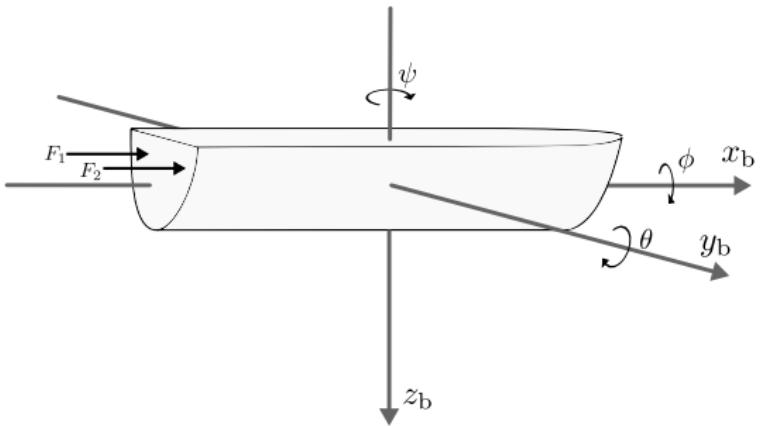
Model Dynamics



- ▶ Rigid Body Dynamics
- ▶ Hydrostatics
- ▶ Hydrodynamics

Model

Rigid Body Dynamics

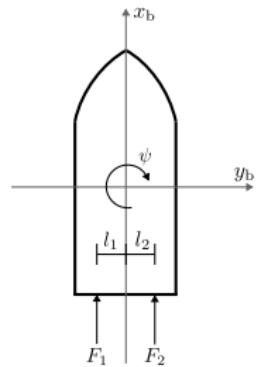
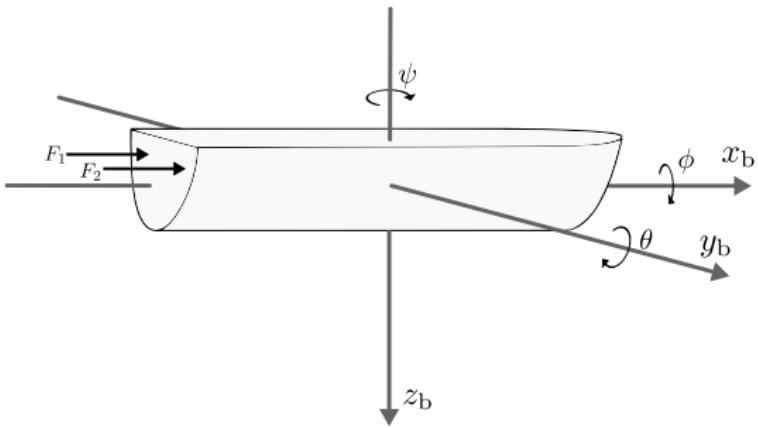


$$\sum F = m\ddot{x}$$

$$\sum \tau = I\ddot{\theta}$$

Model

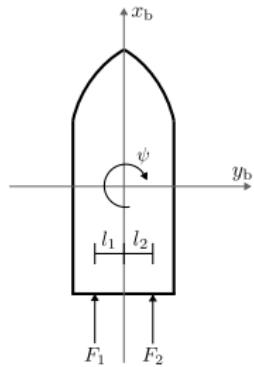
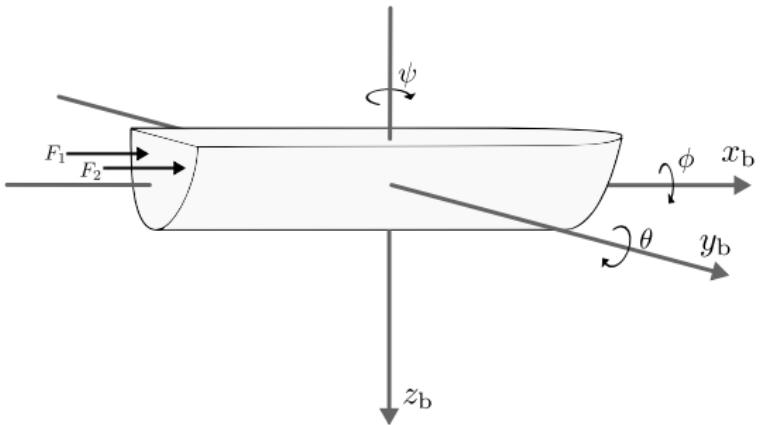
Hydrostatics



- ▶ Buoyancy Force

Model

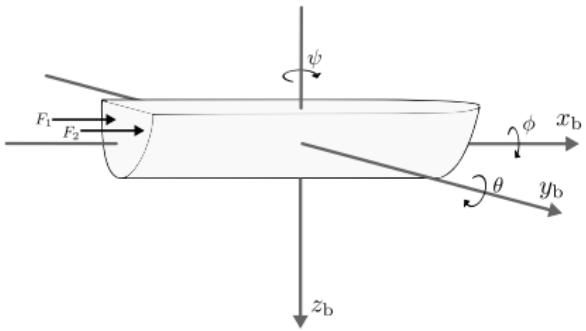
Hydrodynamics



- ▶ Added mass
- ▶ Viscous Damping

Model

Model Equations



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

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

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

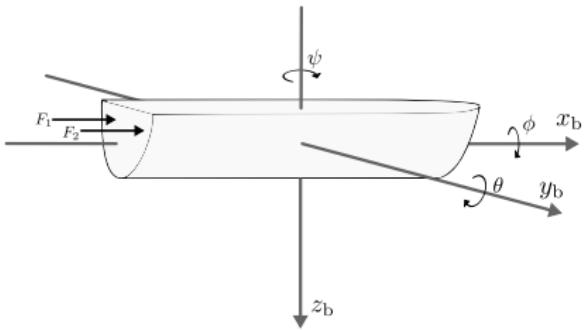
$$I_x \ddot{\phi} = -d_{\dot{\phi}}\dot{\phi} + T_\phi$$

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

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

Model

Linearized Model Equations



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

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

$$m\ddot{z}_b = -d_{\dot{z}_b} \dot{z}_b - \rho g A_w p \tilde{z}_n$$

$$I_x \ddot{\phi} = -d_{\dot{\phi}} \dot{\phi} - \rho g V \overline{GM_T} \cdot \phi$$

$$I_y \ddot{\theta} = -d_{\dot{\theta}} \dot{\theta} - \rho g V \overline{GM_L} \cdot \theta$$

$$I_z \ddot{\psi} = F_1 l_1 - F_2 l_2 - d_{\dot{\psi}} \dot{\psi}$$

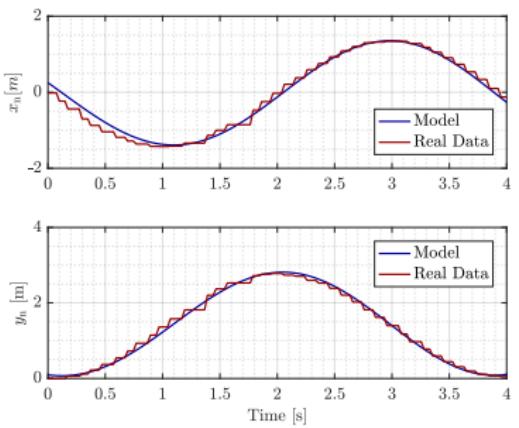
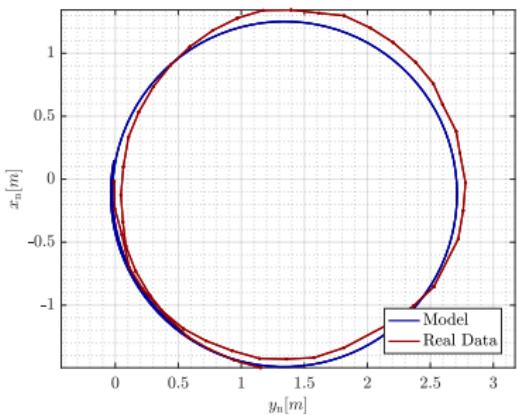
Model

Model Verification



13

► Verified Nonlinear Model

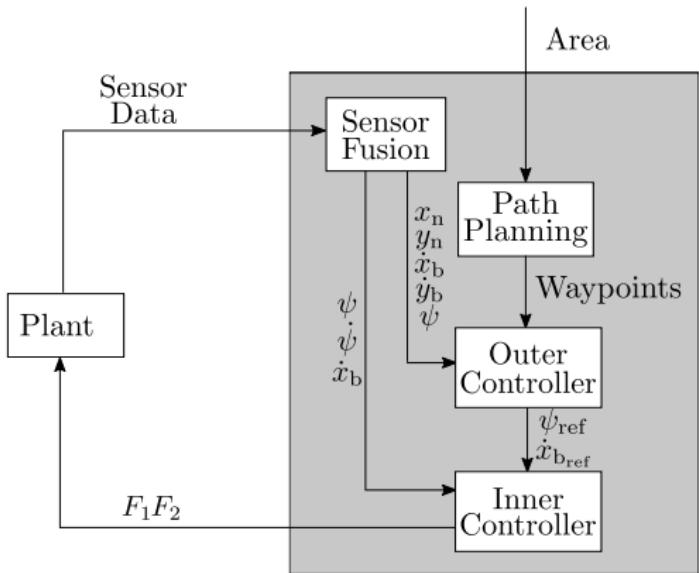


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- ▶ **Control Approach**
- ▶ **Sensor Fusion**
 - Attitude Kalman Filter
 - Position Kalman Filter
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- ▶ Conclusion

Control Approach



Sensor Fusion

Structure



- ▶ Fuses GPS and IMU data
- ▶ Achieved using a Kalman Filter
- ▶ Sensor Fusion Contains
 - ▶ Attitude
 - ▶ Position

Sensor Fusion

Signal Model



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

- ▶ $\mathbf{w}(k)$ and $\mathbf{v}(k)$ are assumed white Gaussian.
- ▶ Covariance matrices \mathbf{Q} and \mathbf{R} holds the respective variances.

Sensor Fusion

Signal Model - State Extension



States are extended to:

- ▶ Attitude:

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

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

- ▶ Position:

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

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

Sensor Fusion

Kalman Filter



- ▶ Step 0: Initialization

$$\hat{\mathbf{x}}_{\text{att}}(0|0) = \mathbf{0}_{6 \times 1} , \quad (1)$$

$$\mathbf{P}_{\text{att}}(0|0) = \mathbf{Q}_{\text{att}} . \quad (2)$$

- ▶ Step 1: Prediction:
- ▶ Step 2: Update:

Sensor Fusion

Kalman Filter



- ▶ Step 0: Initialization
- ▶ Step 1: Prediction:

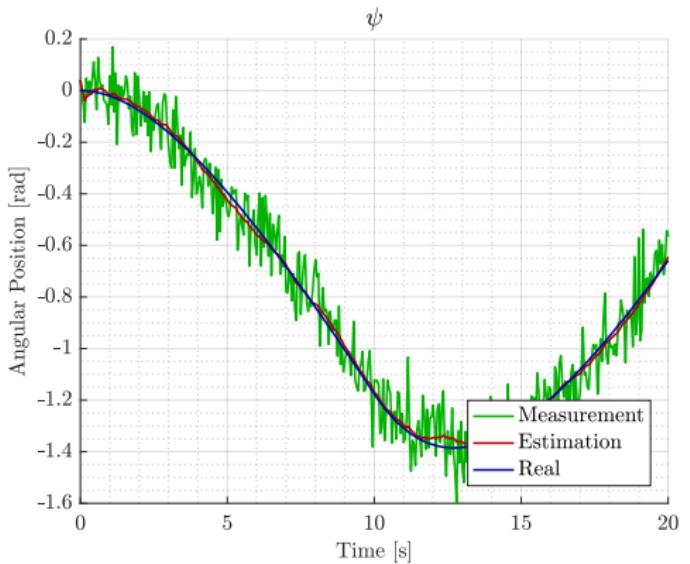
$$\begin{aligned}\hat{\mathbf{x}}(k+1|k) &= \mathbf{A}\hat{\mathbf{x}}(k|k) + \mathbf{B}\mathbf{u}(k) \\ \mathbf{P}(k+1|k) &= \mathbf{A}\mathbf{P}(k|k)\mathbf{A}^T + \mathbf{Q}\end{aligned}$$

- ▶ Step 2: Update:

$$\begin{aligned}\hat{\mathbf{x}}(k+1|k+1) &= \hat{\mathbf{x}}(k+1|k) + \mathbf{K}(k+1) [\mathbf{y}(k+1) - \mathbf{C}\hat{\mathbf{x}}(k+1|k)] \\ \mathbf{P}(k+1|k+1) &= \left[\mathbf{I} - \mathbf{K}(k+1)\mathbf{C}^T \right] \mathbf{P}(k+1|k) \\ \mathbf{K}(k+1) &= \mathbf{P}(k+1|k)\mathbf{C}^T \left[\mathbf{C}\mathbf{P}(k+1|k)\mathbf{C}^T + \mathbf{R} \right]^{-1}\end{aligned}$$

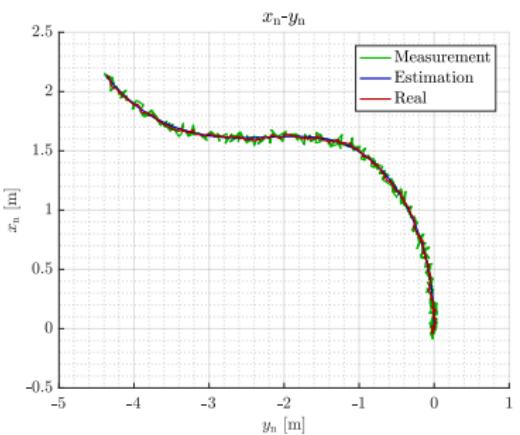
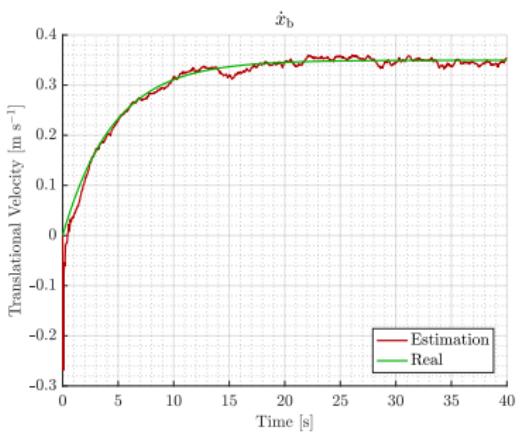
Sensor Fusion

Attitude Kalman Filter



Sensor Fusion

Position Kalman Filter

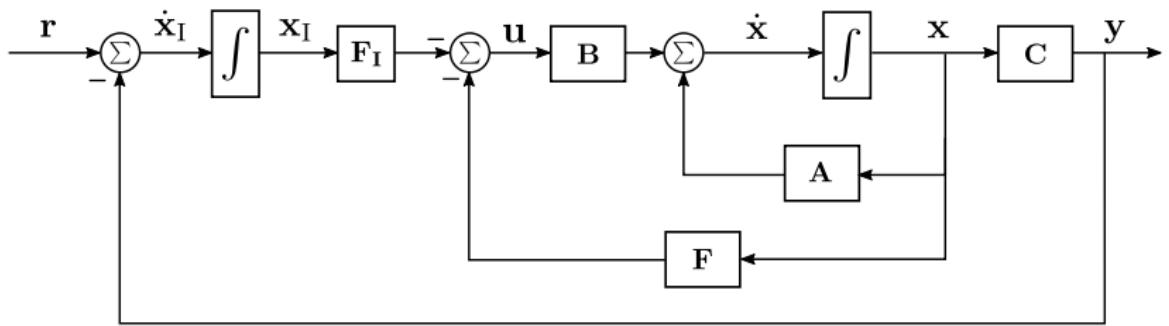


Agenda

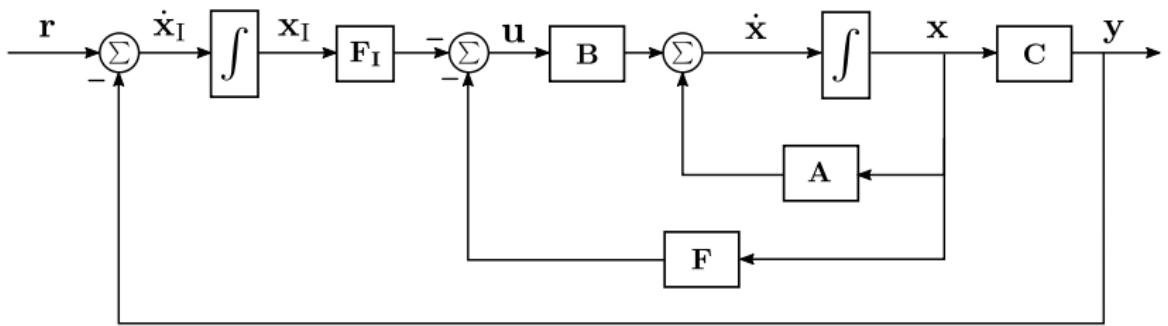


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Inner Controller



Inner Controller



- ▶ Linear Quadratic Regulator
- ▶ \mathcal{H}_∞ Controller

Inner Controller

\mathcal{H}_∞ Controller Design



- ▶ Suboptimal \mathcal{H}_∞ controller

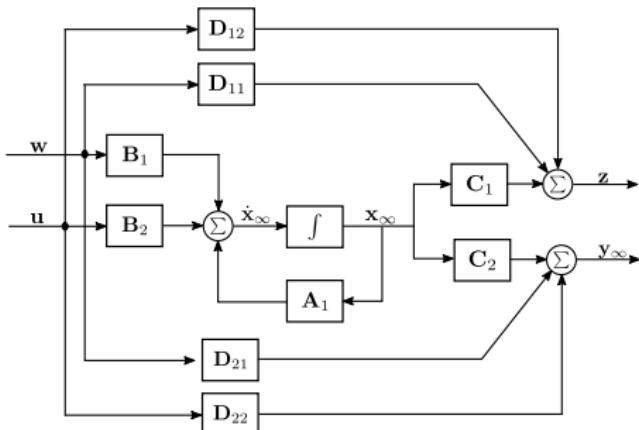
Find an internally stabilizing controller that provides a closed loop \mathcal{H}_∞ norm less than some bound γ

Inner Controller

\mathcal{H}_∞ Controller Design



► System structure



$$\dot{\mathbf{x}}_\infty(t) = \mathbf{A}_1 \mathbf{x}_\infty(t) + \mathbf{B}_1 w(t) + \mathbf{B}_2 u(t)$$

$$\mathbf{z}(t) = \mathbf{C}_1 \mathbf{x}_\infty(t) + \mathbf{D}_{11} w(t) + \mathbf{D}_{12} u(t)$$

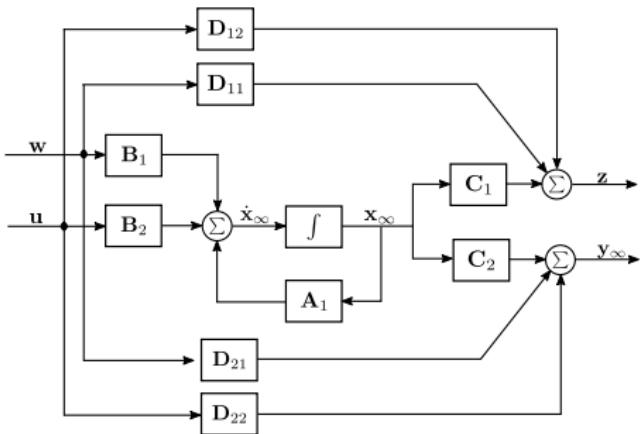
$$\mathbf{y}_\infty(t) = \mathbf{C}_2 \mathbf{x}_\infty(t) + \mathbf{D}_{21} w(t) + \mathbf{D}_{22} u(t)$$

Inner Controller

\mathcal{H}_∞ Controller Design



► System structure



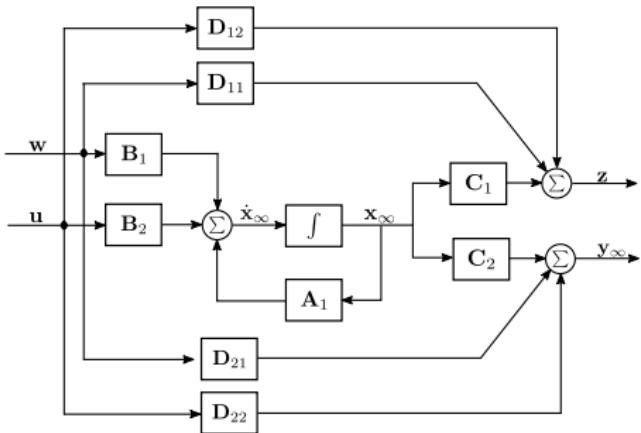
$$\mathbf{u}(t) = [F_1 \quad F_2]^T$$

Inner Controller

\mathcal{H}_∞ Controller Design



► System structure



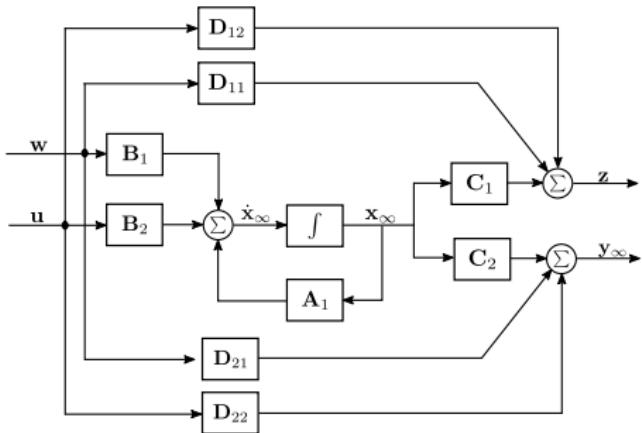
$$\mathbf{w}(t) = [\psi_{\text{ref}} \quad \dot{x}_{\text{b,ref}} \quad F_{\text{wc}} \quad \tau_{\text{wc}} \quad F_{\text{wave}} \quad \tau_{\text{wave}} \quad n_{\psi} \quad n_{\dot{x}_{\text{b}}}]^T$$

Inner Controller

\mathcal{H}_∞ Controller Design



► System structure



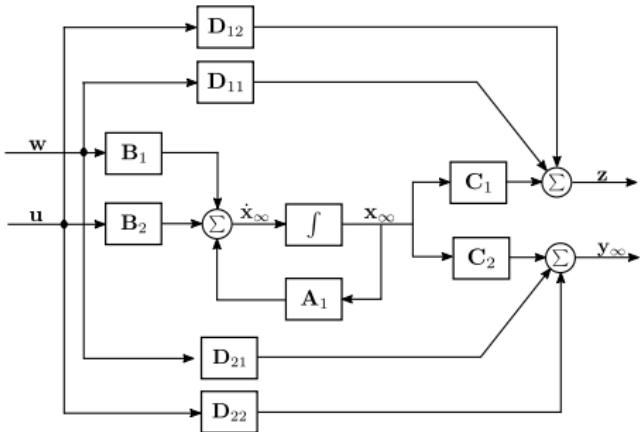
$$\mathbf{y}_\infty(t) = [\psi \quad \dot{x}_b \quad \mathbf{x}_I^T]^T$$

Inner Controller

\mathcal{H}_∞ Controller Design



► System structure



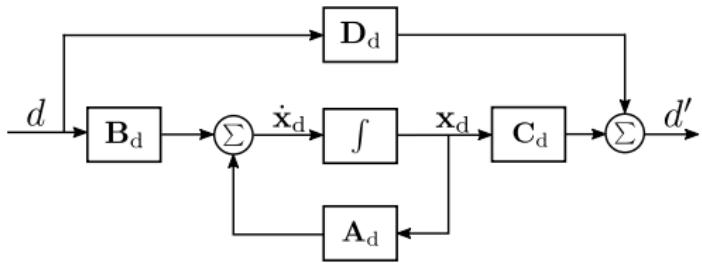
$$\mathbf{x}_\infty(t) = \begin{bmatrix} \psi & \dot{\psi} & \dot{x}_b & x_{int_\psi} & x_{int_{\dot{x}_b}} & x_{F_{wc}} & x_{T_{wc}} & x_{F_{wave}} & x_{T_{wave}} & x_{n_\psi} & x_{n_{\dot{x}_b}} \end{bmatrix}^T$$

Inner Controller

\mathcal{H}_∞ Controller Design



- ▶ Disturbance model



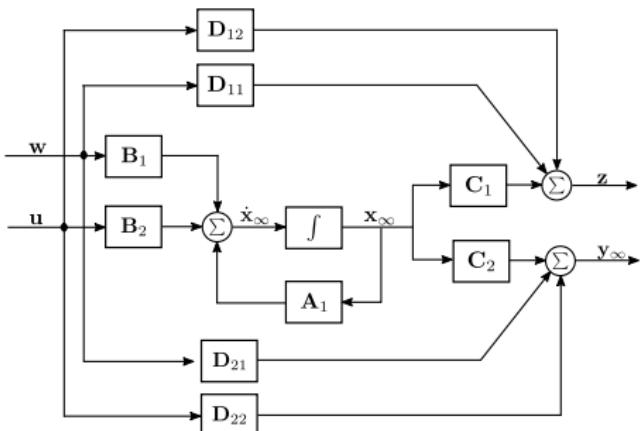
$$\frac{d'}{d} = \frac{a}{s+a} \rightarrow \dot{d}' = -ad' + ad \rightarrow \begin{cases} \dot{x}_d = -ax_d + ad \\ d' = x_d \end{cases}$$

Inner Controller

\mathcal{H}_∞ Controller Design



► System structure



$$\mathbf{z}(t) = [\mathbf{x}_\infty^T \quad \mathbf{u}^T]^T$$

Inner Controller

\mathcal{H}_∞ Controller Design



- Controller design parameters (γ , \mathbf{C}_1 , \mathbf{D}_{12})

$$\mathbf{C}_1 = \begin{bmatrix} \mathbf{W}_x & \mathbf{0}_{3 \times 2} & \mathbf{0}_{3 \times 2} & \mathbf{0}_{3 \times 2} & \mathbf{0}_{3 \times 2} \\ \mathbf{0}_{2 \times 3} & \mathbf{W}_I & \mathbf{0}_{2 \times 2} & \mathbf{0}_{2 \times 2} & \mathbf{0}_{2 \times 2} \\ \mathbf{0}_{2 \times 3} & \mathbf{0}_{2 \times 2} & \mathbf{W}_{w_c} & \mathbf{0}_{2 \times 2} & \mathbf{0}_{2 \times 2} \\ \mathbf{0}_{2 \times 3} & \mathbf{0}_{2 \times 2} & \mathbf{0}_{2 \times 2} & \mathbf{W}_{wave} & \mathbf{0}_{2 \times 2} \\ \mathbf{0}_{2 \times 3} & \mathbf{0}_{2 \times 2} & \mathbf{0}_{2 \times 2} & \mathbf{0}_{2 \times 2} & \mathbf{W}_{noise} \\ \mathbf{0}_{2 \times 3} & \mathbf{0}_{2 \times 2} & \mathbf{0}_{2 \times 2} & \mathbf{0}_{2 \times 2} & \mathbf{0}_{2 \times 2} \\ \mathbf{0}_{2 \times 3} & \mathbf{0}_{2 \times 2} & \mathbf{0}_{2 \times 2} & \mathbf{0}_{2 \times 2} & \mathbf{0}_{2 \times 2} \end{bmatrix} \quad \mathbf{D}_{12} = \begin{bmatrix} \mathbf{0}_{2 \times 3} \\ \mathbf{0}_{2 \times 2} \\ \mathbf{0}_{2 \times 2} \\ \mathbf{0}_{2 \times 2} \\ \mathbf{0}_{2 \times 2} \\ \mathbf{W}_u \end{bmatrix}$$

Inner Controller

\mathcal{H}_∞ Controller Design



- ▶ Feedback gain

$$\mathbf{X}_\infty = Ric \begin{bmatrix} \mathbf{A} & \gamma^{-2} \mathbf{B}_1 \mathbf{B}_1^T - \mathbf{B}_2 \mathbf{B}_2^T \\ -\mathbf{C}_1^T \mathbf{C}_1 & -\mathbf{A}^T \end{bmatrix}$$

$$\mathbf{F}_\infty = -\mathbf{B}_2^T \mathbf{X}_\infty$$

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Inner Controller

Linear Quadratic Controller Design



Inner Controller

Comparison of the Controllers



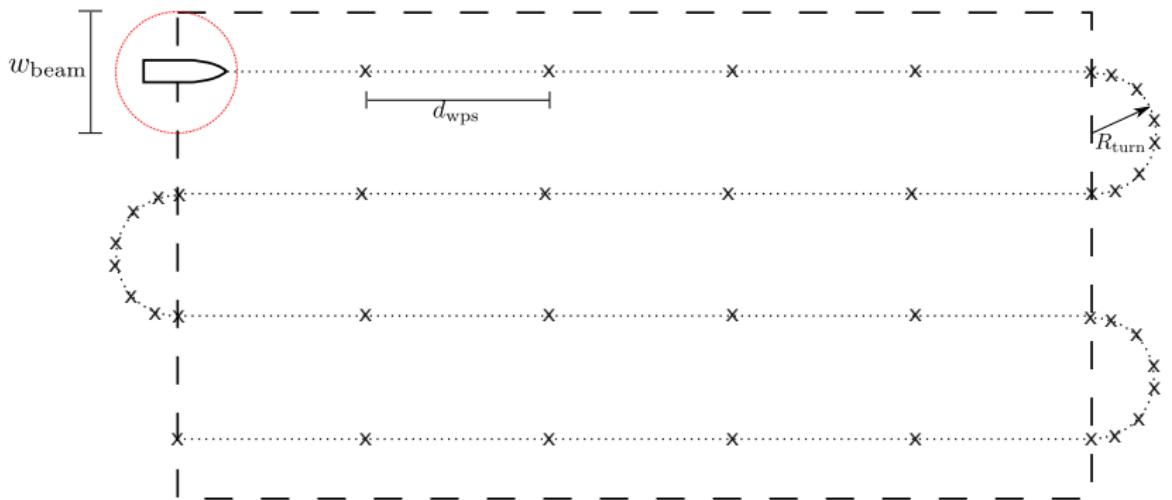
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- ▶ **Outer Controller**
 - Path Generation Algorithm
 - Path Following Algorithm
- ▶ **Results**
 - Controller Results
 - Implementation Results
- ▶ **Conclusion**

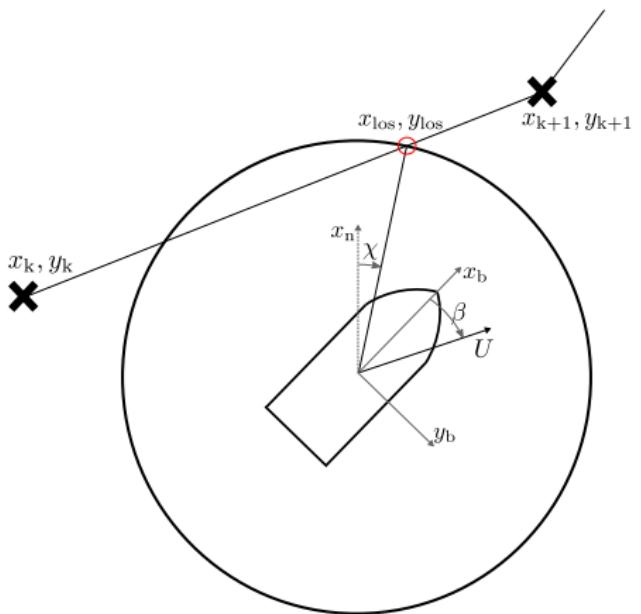
Outer Controller

Path Generation Algorithm



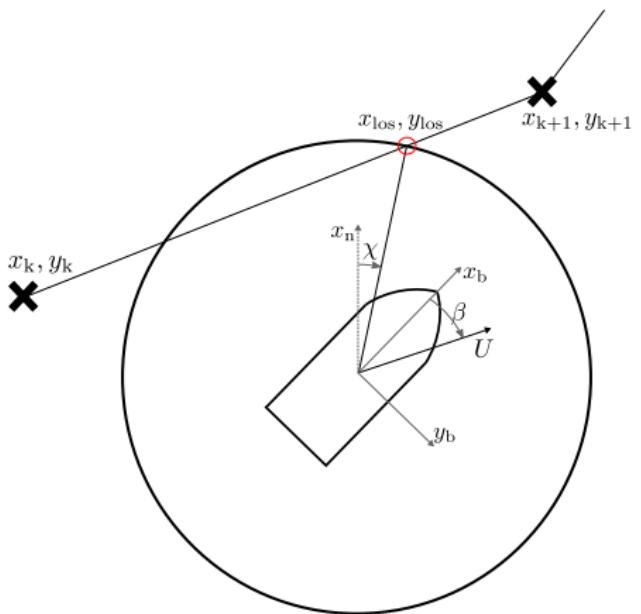
Outer Controller

Path Following Algorithm



Outer Controller

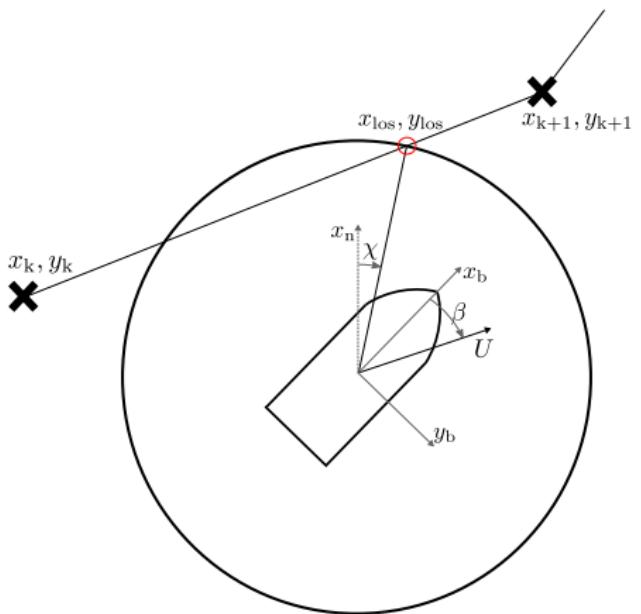
Path Following Algorithm



$$\chi = \arctan \left(\frac{y_{\text{LOS}} - y_n}{x_{\text{LOS}} - x_n} \right)$$

Outer Controller

Path Following Algorithm

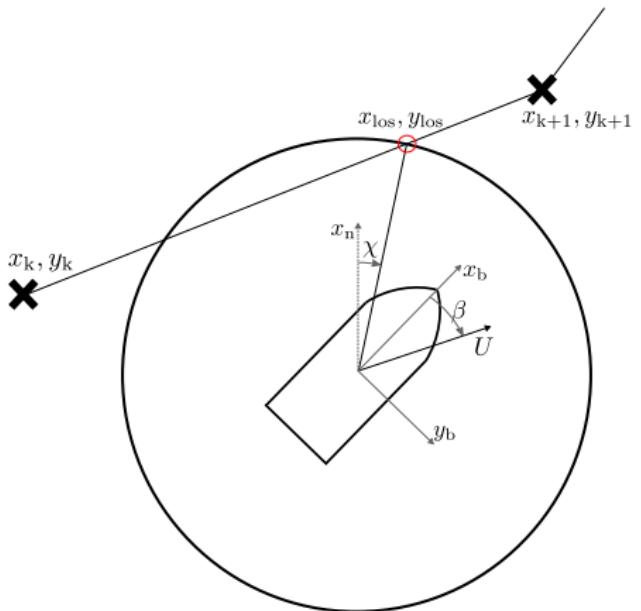


$$\chi = \arctan \left(\frac{y_{\text{LOS}} - y_n}{x_{\text{LOS}} - x_n} \right)$$

$$\beta = \arctan \left(\frac{\dot{y}_b}{\dot{x}_b} \right)$$

Outer Controller

Path Following Algorithm



$$\chi = \arctan \left(\frac{y_{\text{LOS}} - y_n}{x_{\text{LOS}} - x_n} \right)$$

$$\beta = \arctan \left(\frac{\dot{y}_b}{\dot{x}_b} \right)$$

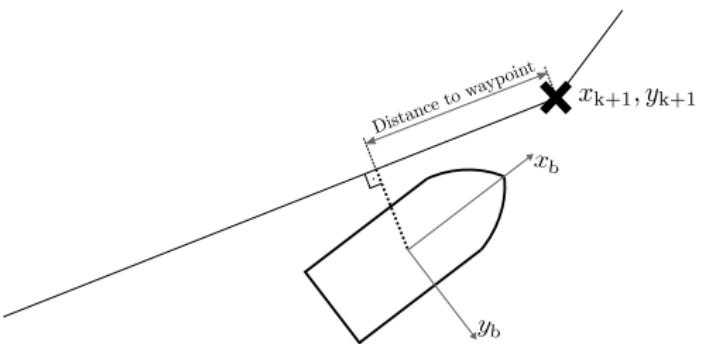
$$\psi_{\text{ref}} = \chi - \beta$$

Outer Controller

Path Following Algorithm



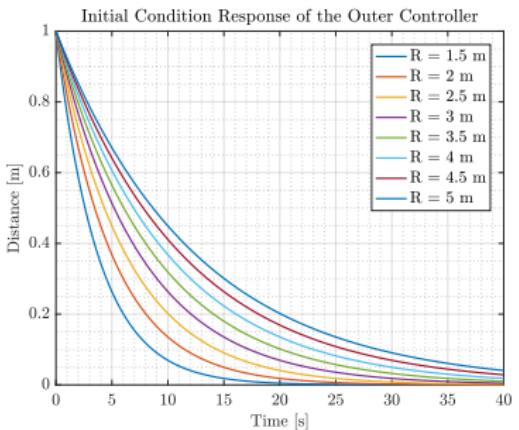
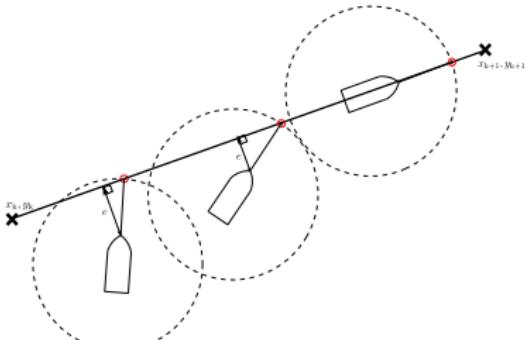
- ▶ Change active waypoints



Outer Controller

Path Following Algorithm

- ▶ Convergence to the path

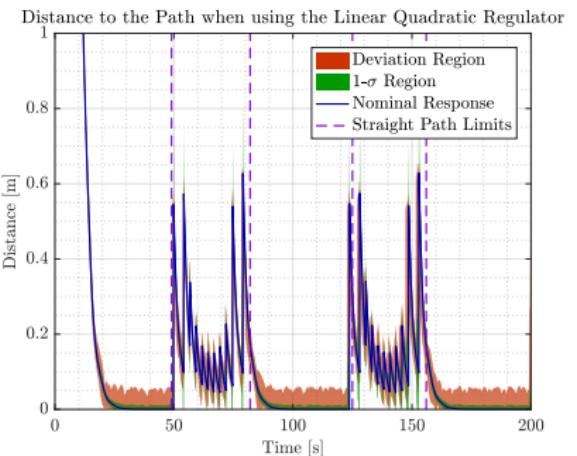
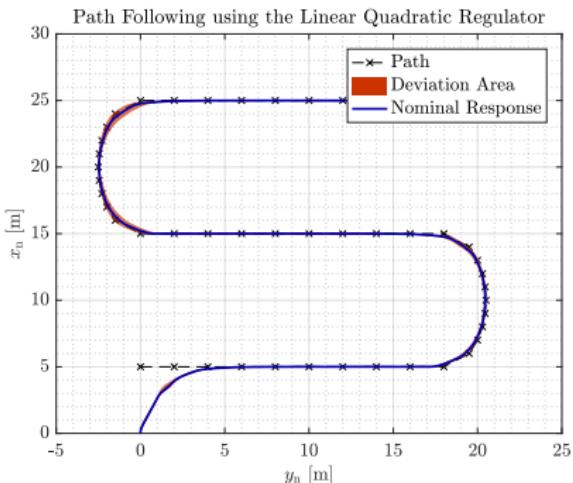


Results

Controller Results



► LQR as inner controller

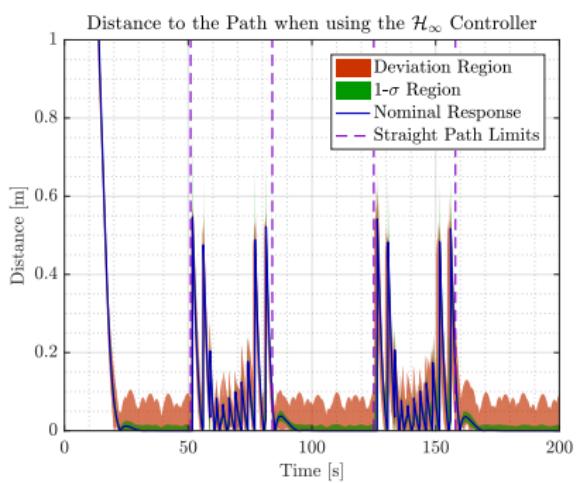
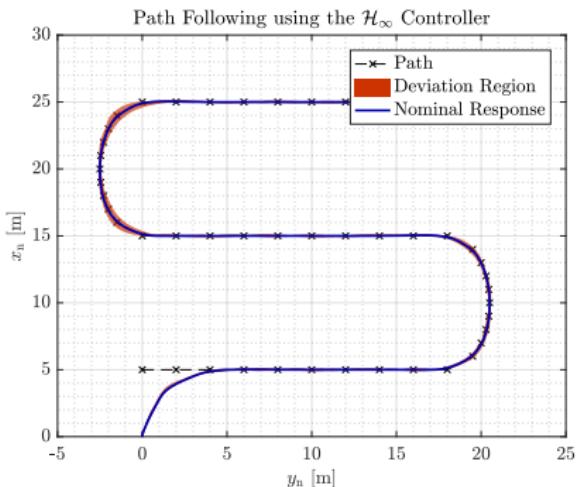


Results

Controller Results



- ▶ Robust controller as inner controller

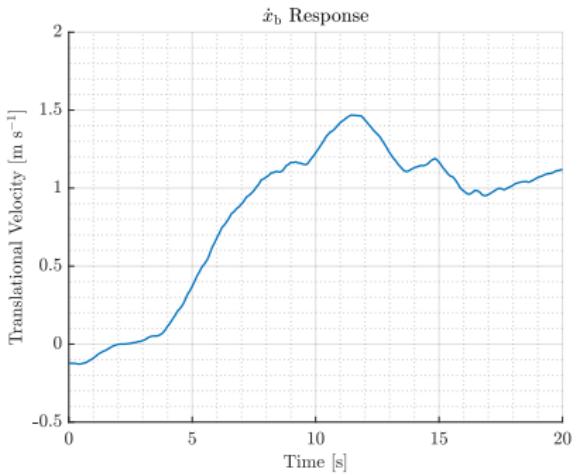
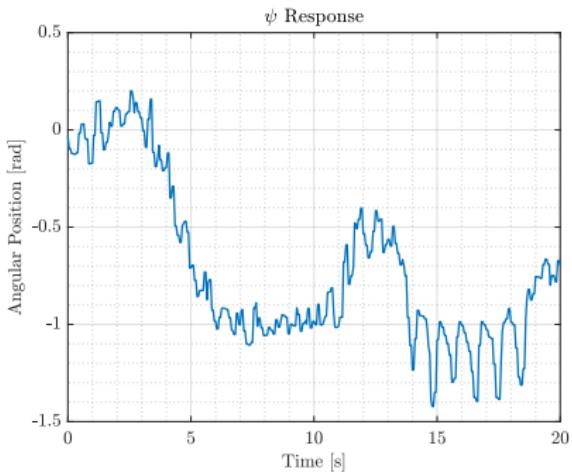


Results

Implementation Results



► Inner controller test



Conclusion



- ▶ The estimator has been tuned and tested through simulation.
- ▶ The controller has also been analyzed though simulations that include disturbances, noise and varying parameters.
- ▶ The simulated results have not been fully replicated in the real vessel, but they show a promising behavior of the control system.

Precision Control of an Autonomous Surface Vessel



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