

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

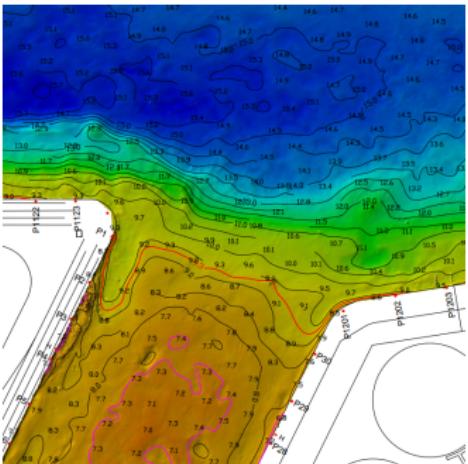
Introduction



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

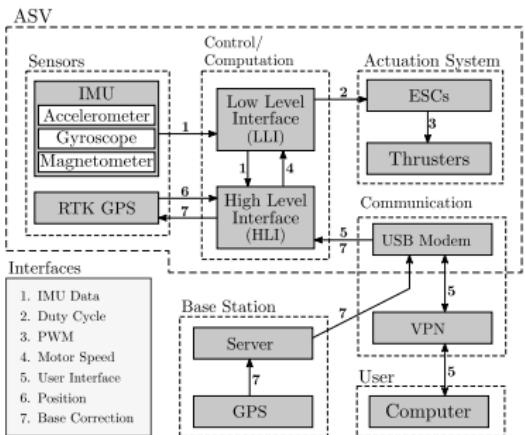
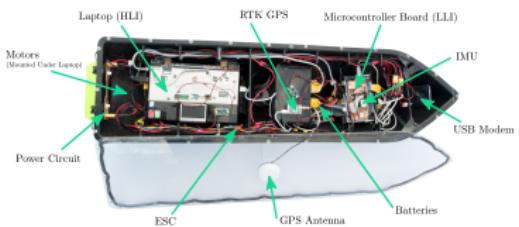
Introduction

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

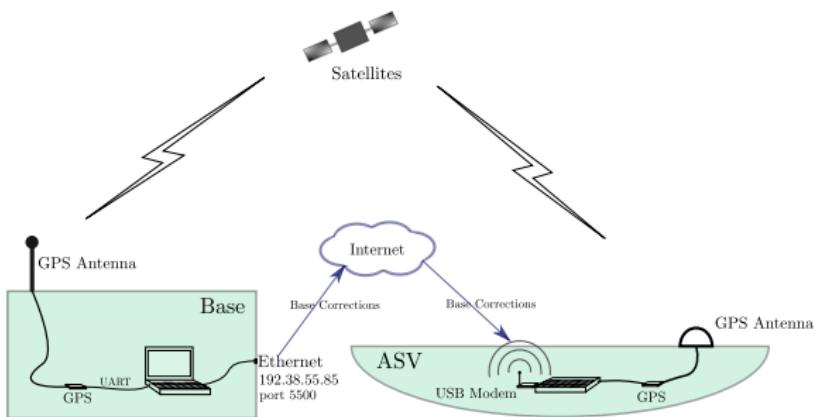


System Description

RTK GPS

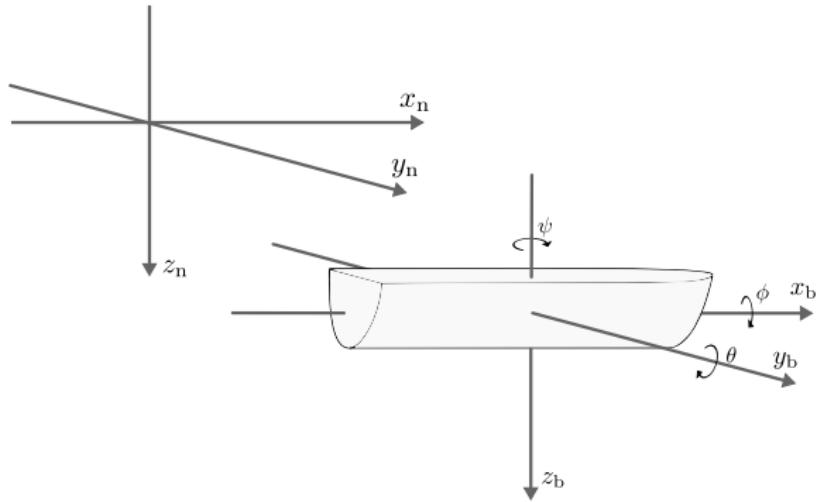


6



Model

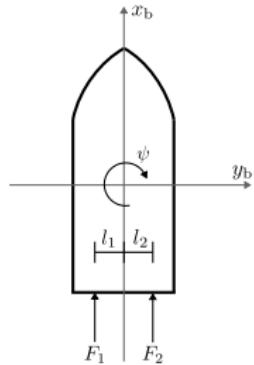
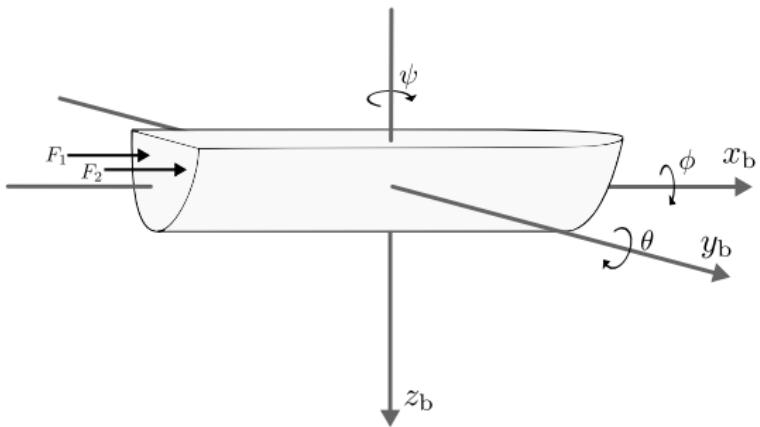
Reference Frames



- ▶ Inertial Frame
- ▶ Body Frame

Model

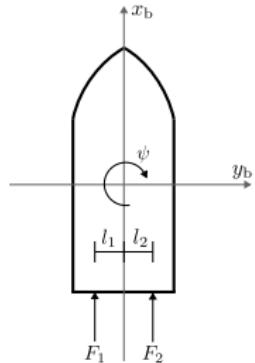
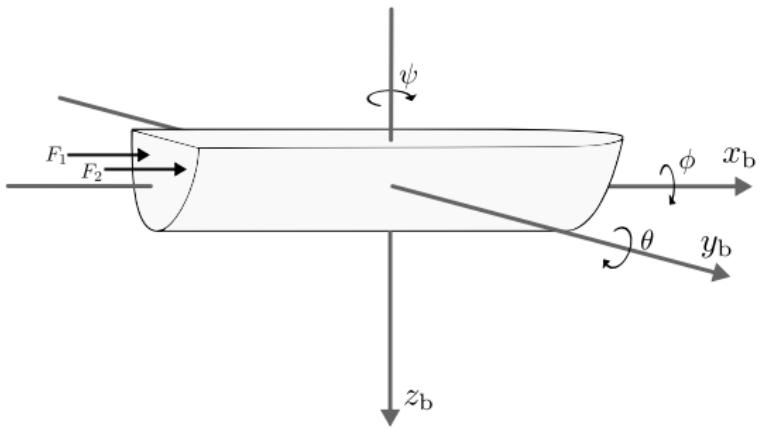
Model Dynamics



- ▶ Rigid Body Dynamics
- ▶ Hydrostatics
- ▶ Hydrodynamics

Model

Rigid Body Dynamics

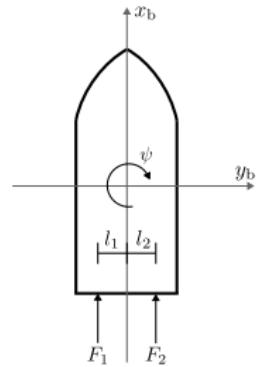
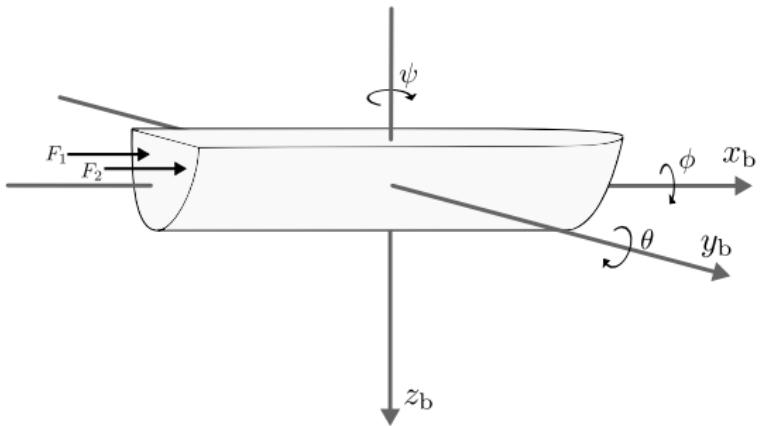


$$\sum F = m\ddot{x}$$

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

Model

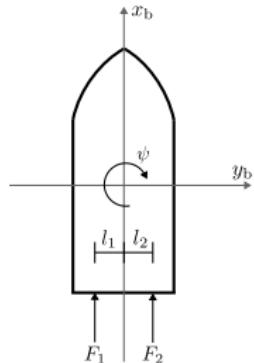
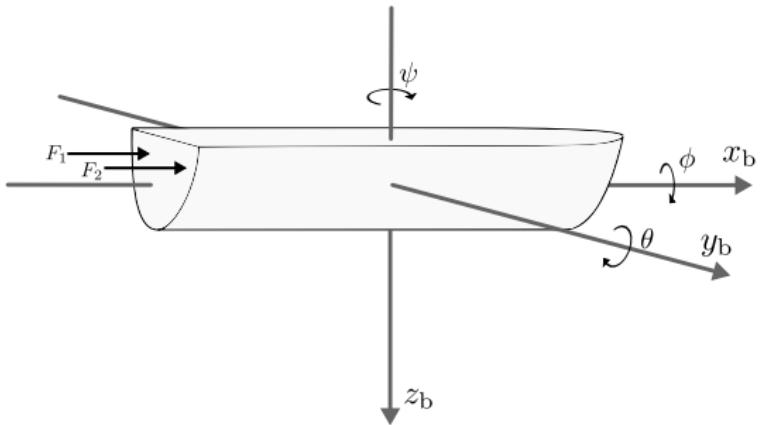
Hydrostatics



- ▶ Buoyancy Force

Model

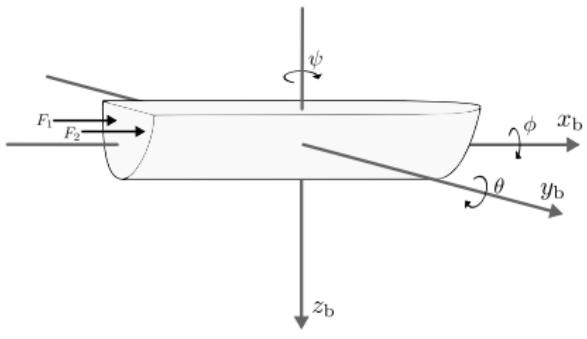
Hydrodynamics



- ▶ Added mass
- ▶ Viscous Damping

Model

Model Equations



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

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

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

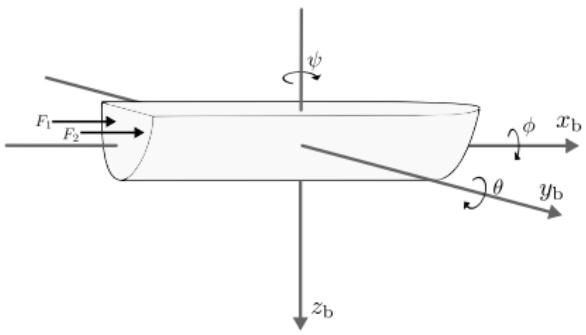
$$I_x \ddot{\phi} = -d_{\dot{\phi}} \dot{\phi} + T_\phi$$

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

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

Model

Linearized Model Equations



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

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

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

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

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

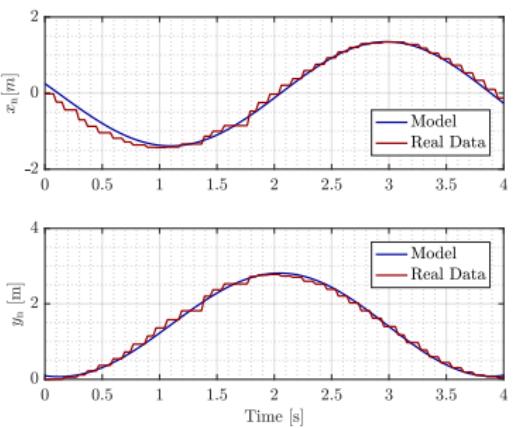
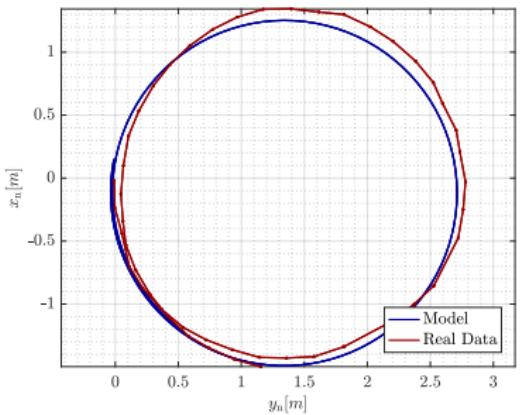
$$I_z \ddot{\psi} = F_1 I_1 - F_2 I_2 - d_{\dot{\psi}} \dot{\psi}$$

Model

Model Verification



► Verified Nonlinear Model

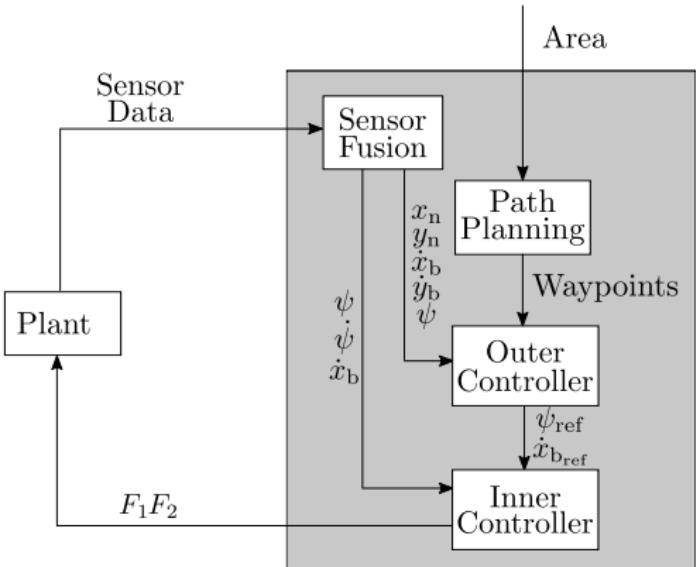


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- ▶ **Sensor Fusion**
 - Attitude Kalman Filter
 - Position Kalman Filter
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- ▶ Outer Controller
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Control Approach



Sensor Fusion

Structure



- ▶ Fuses GPS and IMU data
- ▶ Achieved using a Kalman filter
- ▶ Sensor fusion contains
 - ▶ Attitude
 - ▶ Position

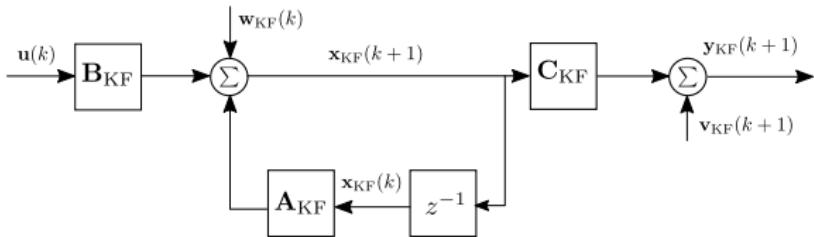
Sensor Fusion

Signal Model



$$\mathbf{x}_{\text{KF}}(k+1) = \mathbf{Ax}_{\text{KF}}(k) + \mathbf{B}_{\text{KF}}\mathbf{u}(k) + \mathbf{w}_{\text{KF}}(k)$$

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



- ▶ $w(k)$ and $v(k)$ are assumed white Gaussian
- ▶ Matrices \mathbf{Q}_{KF} and \mathbf{R}_{KF} contain the respective covariances

Sensor Fusion

Signal Model - State and Measurement Vectors



► Attitude

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

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

► Position

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

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

Sensor Fusion

Kalman Filter



- ▶ Step 0: Initialization

$$\hat{\mathbf{x}}_{\text{KF}}(0|0) = \mathbf{0}$$

$$\mathbf{P}_{\text{KF}}(0|0) = \mathbf{Q}_{\text{KF}}$$

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

Sensor Fusion

Kalman Filter



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

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

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

- ▶ Step 2: Update

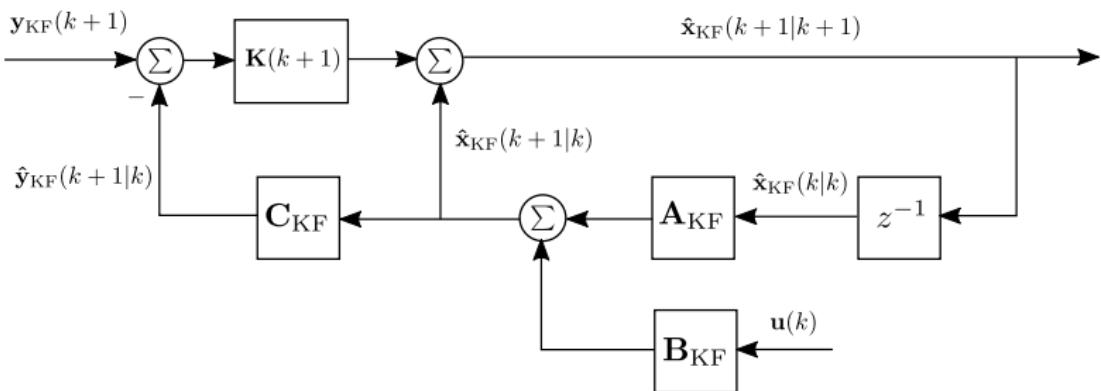
$$\hat{\mathbf{x}}_{\text{KF}}(k+1|k+1) = \hat{\mathbf{x}}_{\text{KF}}(k+1|k) + \mathbf{K}(k+1) [\mathbf{y}_{\text{KF}}(k+1) - \mathbf{C}_{\text{KF}} \hat{\mathbf{x}}_{\text{KF}}(k+1|k)]$$

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

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

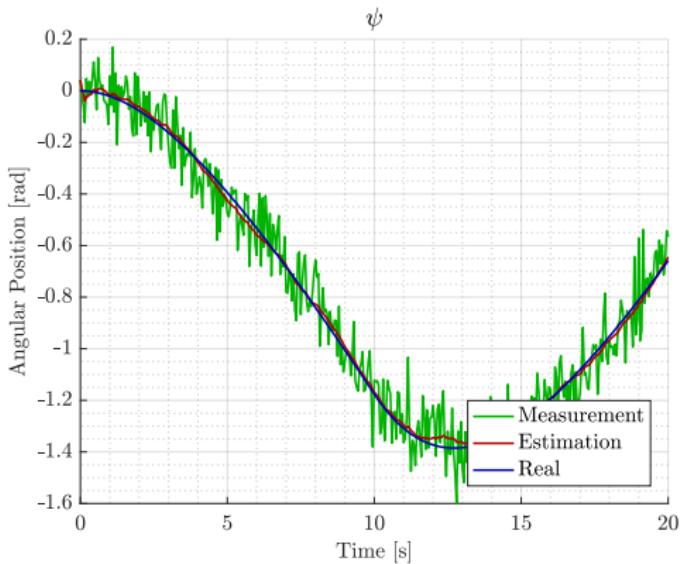
Sensor Fusion

Kalman Filter



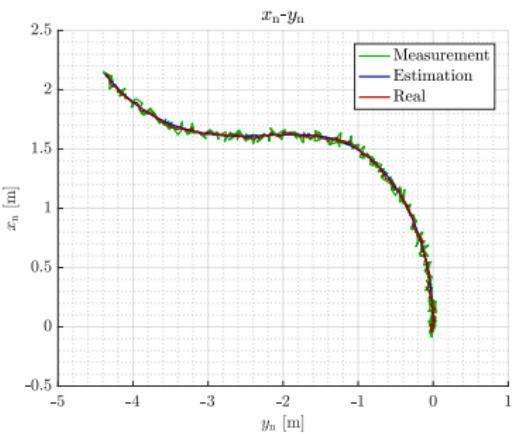
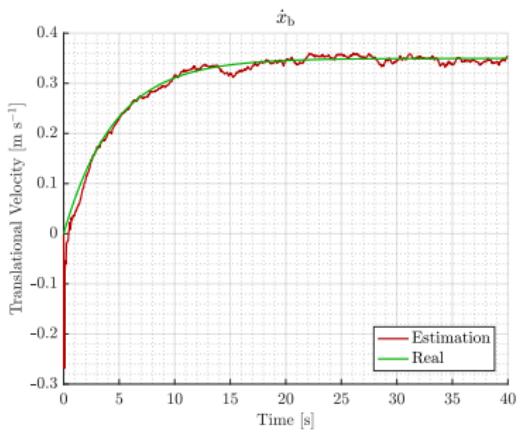
Sensor Fusion

Attitude Kalman Filter



Sensor Fusion

Position Kalman Filter

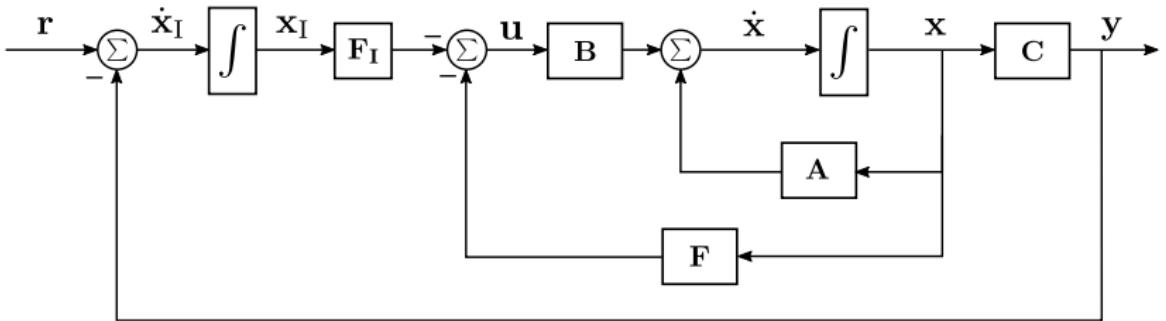


Agenda

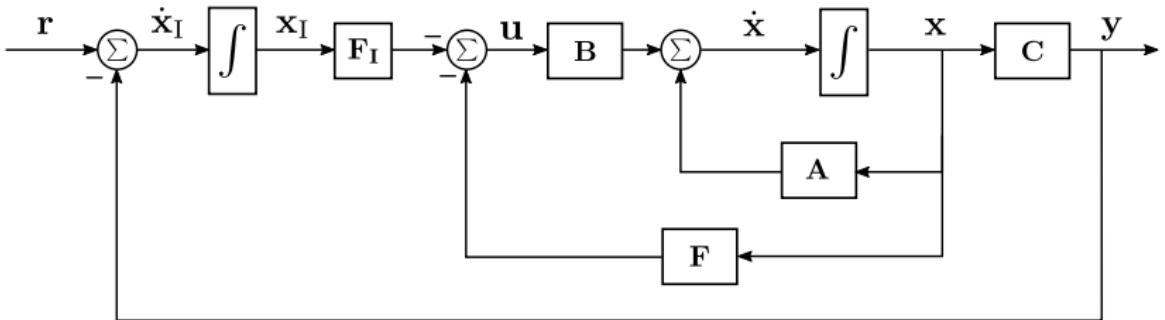


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Inner Controller



Inner Controller



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

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

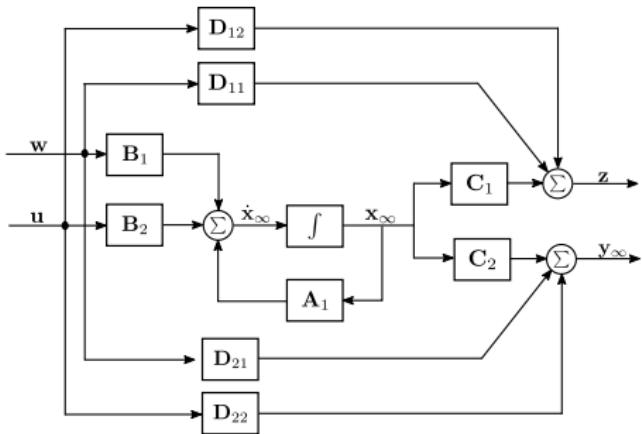
Inner Controller

\mathcal{H}_∞ Controller Design



28

► System structure



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

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

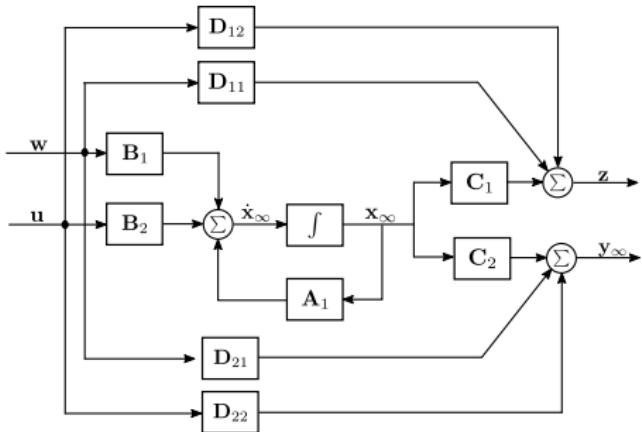
$$\mathbf{y}_\infty(t) = \mathbf{C}_2 \mathbf{x}_\infty(t) + \mathbf{D}_{21} \mathbf{w}(t) + \mathbf{D}_{22} \mathbf{u}(t)$$

Inner Controller

\mathcal{H}_∞ Controller Design



► System structure



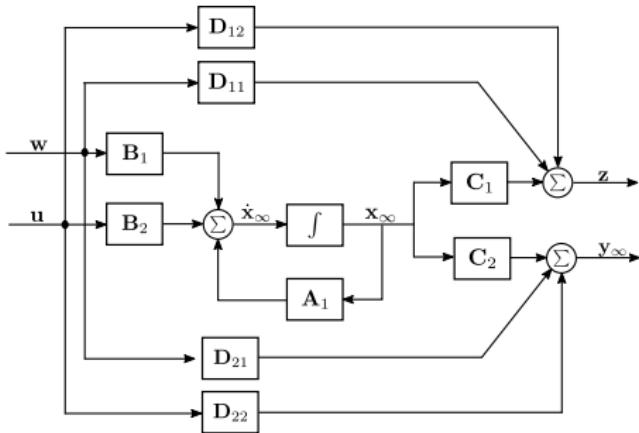
$$\mathbf{u}(t) = [F_1 \quad F_2]^T$$

Inner Controller

\mathcal{H}_∞ Controller Design



► System structure



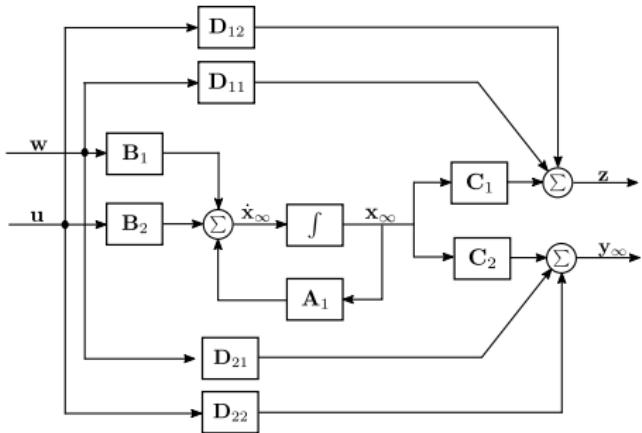
$$\mathbf{w}(t) = [\psi_{\text{ref}} \quad \dot{x}_{\text{b,ref}} \quad F_{\text{wc}} \quad \tau_{\text{wc}} \quad F_{\text{wave}} \quad \tau_{\text{wave}} \quad n_\psi \quad n_{\dot{x}_{\text{b}}}]^T$$

Inner Controller

\mathcal{H}_∞ Controller Design



► System structure



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

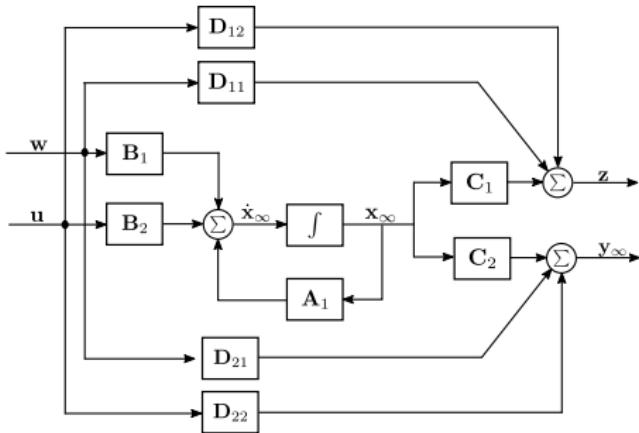
Inner Controller

\mathcal{H}_∞ Controller Design



28

► System structure



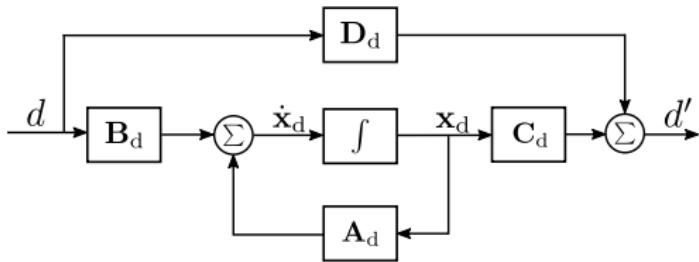
$$\mathbf{x}_\infty(t) = \begin{bmatrix} \psi & \dot{\psi} & \dot{x}_b & x_{I_\psi} & x_{I_{\dot{x}_b}} & x_{F_{wc}} & x_{\tau_{wc}} & x_{F_{wave}} & x_{\tau_{wave}} & x_{n_\psi} & x_{n_{\dot{x}_b}} \end{bmatrix}^T$$

Inner Controller

\mathcal{H}_∞ Controller Design



- ▶ Disturbance model



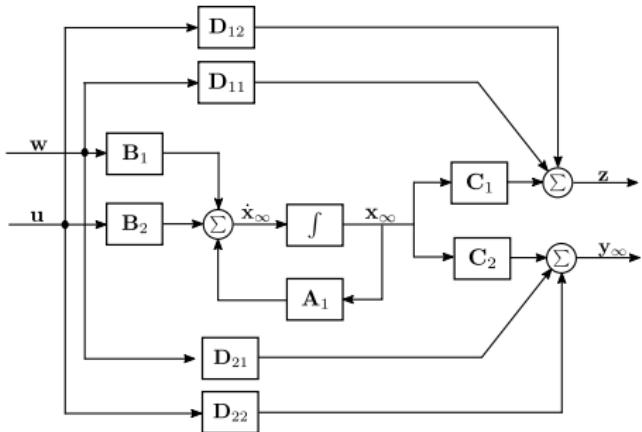
$$\frac{d'}{d} = \frac{a}{s+a} \rightarrow \dot{d}' = -ad' + ad \rightarrow \begin{cases} \dot{x}_d = -ax_d + ad \\ d' = x_d \end{cases}$$

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



31

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

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

Inner Controller

\mathcal{H}_∞ Controller Design



- ▶ Feedback gain

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

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

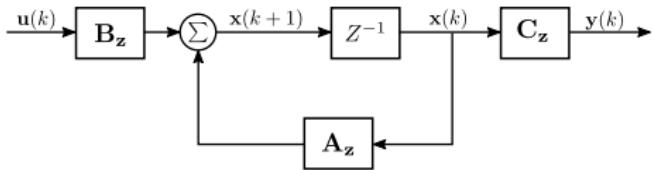
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Inner Controller

Linear Quadratic Controller Design

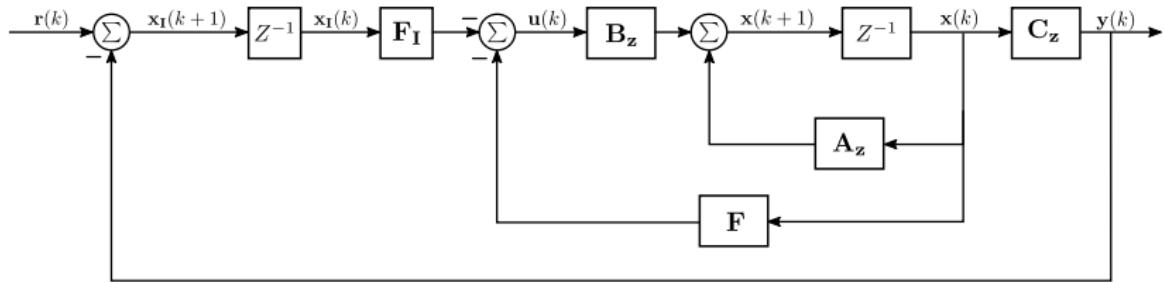


$$\mathbf{x}(k+1) = \mathbf{A}_z \mathbf{x}(k) + \mathbf{B}_z \mathbf{u}(k)$$

$$\mathbf{y}(k) = \mathbf{C}_z \mathbf{x}(k) + \mathbf{D}_z \mathbf{u}(k)$$

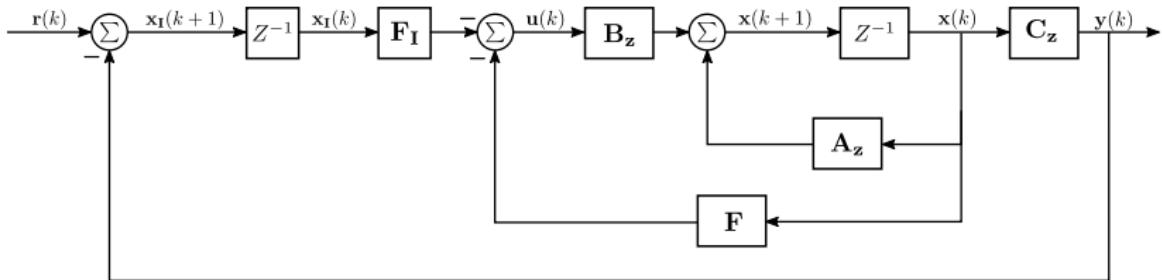
Inner Controller

Linear Quadratic Controller Design



Inner Controller

Linear Quadratic Controller Design



$$\mathbf{x}_e(k+1) = \mathbf{A}_e \mathbf{x}_e(k) + \mathbf{B}_e \mathbf{u}(k) + \mathbf{r}(k)$$

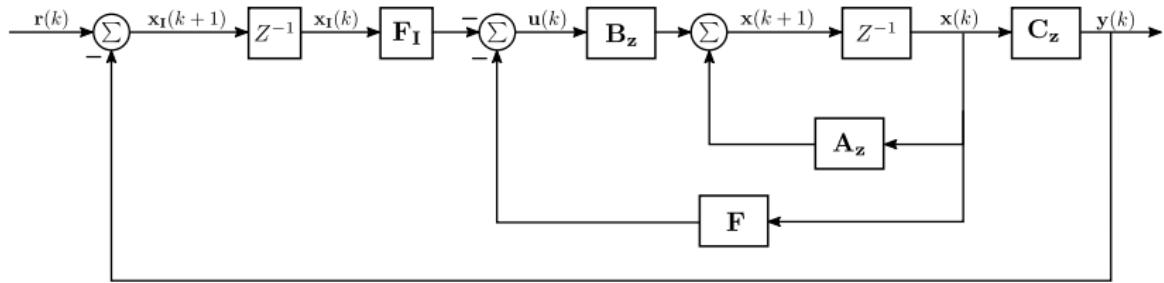
$$\mathbf{y}(k) = \mathbf{C}_e \mathbf{x}_e(k)$$

Inner Controller

Linear Quadratic Controller Design



34



$$\begin{bmatrix} \mathbf{x}(k+1) \\ \mathbf{x}_I(k+1) \end{bmatrix} = \begin{bmatrix} \mathbf{A}_{z,3 \times 3} & \mathbf{0}_{3 \times 2} \\ -\mathbf{C}_{z,2 \times 3} & \mathbf{I}_{2 \times 2} \end{bmatrix} \begin{bmatrix} \mathbf{x}(k) \\ \mathbf{x}_I(k) \end{bmatrix} + \begin{bmatrix} \mathbf{B}_{z,3 \times 2} \\ \mathbf{0}_{2 \times 2} \end{bmatrix} \mathbf{u}(k) + \begin{bmatrix} \mathbf{0}_{3 \times 2} \\ \mathbf{I}_{2 \times 2} \end{bmatrix} \mathbf{r}(k)$$

$$\mathbf{y}(k) = [\mathbf{C}_{z,2 \times 3} \quad \mathbf{0}_{2 \times 2}] \begin{bmatrix} \mathbf{x}(k) \\ \mathbf{x}_I(k) \end{bmatrix}$$

Inner Controller

Linear Quadratic Controller Design



$$\mathcal{J}_z = \sum_{k=0}^{\infty} \mathbf{x}^T(k) \mathbf{Q}_z \mathbf{x}(k) + \mathbf{u}^T(k) \mathbf{R}_z \mathbf{u}(k)$$

Inner Controller

Linear Quadratic Controller Design



$$\mathcal{J} = \int_0^{\infty} \mathbf{x}^T(t) \mathbf{Q} \mathbf{x}(t) + \mathbf{u}^T(t) \mathbf{R} \mathbf{u}(t) \ dt$$

Inner Controller

Linear Quadratic Controller Design



$$\mathcal{J} = \int_0^{\infty} \mathbf{x}^T(t) \mathbf{Q} \mathbf{x}(t) + \mathbf{u}^T(t) \mathbf{R} \mathbf{u}(t) \, dt$$

$$Q = \left(\frac{1}{\psi_{\max}^2}, \frac{1}{\dot{\psi}_{\max}^2}, \frac{1}{\dot{x}_{b,\max}^2}, \frac{1}{x_{I,\psi,\max}^2}, \frac{1}{x_{I,\dot{\psi},\max}^2}, \frac{1}{x_{I,\dot{x}_b,\max}^2} \right)$$

Inner Controller

Linear Quadratic Controller Design



$$\mathcal{J} = \int_0^{\infty} \mathbf{x}^T(t) \mathbf{Q} \mathbf{x}(t) + \mathbf{u}^T(t) \mathbf{R} \mathbf{u}(t) \, dt$$

$$Q = \left(\frac{1}{\psi_{\max}^2}, \frac{1}{\dot{\psi}_{\max}^2}, \frac{1}{\dot{x}_{b,\max}^2}, \frac{1}{x_{I,\psi,\max}^2}, \frac{1}{x_{I,\dot{\psi},\max}^2}, \frac{1}{x_{I,\dot{x}_b,\max}^2} \right)$$

$$R = \left(\frac{1}{F_{1\max}^2}, \frac{1}{F_{2\max}^2} \right)$$

Inner Controller

Comparison of the Controllers



Simulation of LQR and robust design

- ▶ Disturbances from wind and waves
 - ▶ ± 1.5 N along \dot{x}_b
 - ▶ ± 1.5 N·m around z_b
 - ▶ The frequency for both varies between 0-10 Hz

Inner Controller

Comparison of the Controllers



Simulation of LQR and robust design

- ▶ Disturbances from wind and waves
 - ▶ ± 1.5 N along \dot{x}_b
 - ▶ ± 1.5 N·m around z_b
 - ▶ The frequency for both varies between 0-10 Hz
- ▶ The parameters are varied $\pm 20\%$
 - ▶ Mass, m
 - ▶ Moment of inertia, I_z , around z_b
 - ▶ The damping coefficients d_x and d_y
 - ▶ The lengths l_1 and l_2

Inner Controller

Comparison of the Controllers

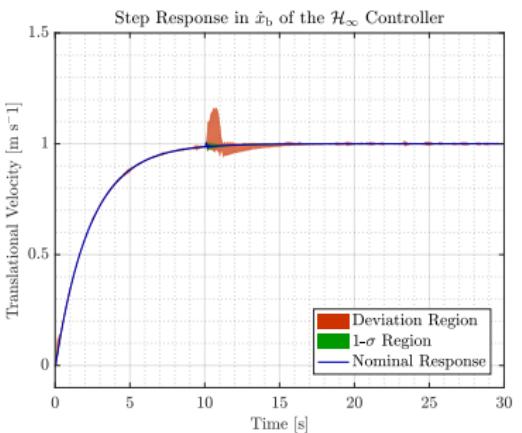
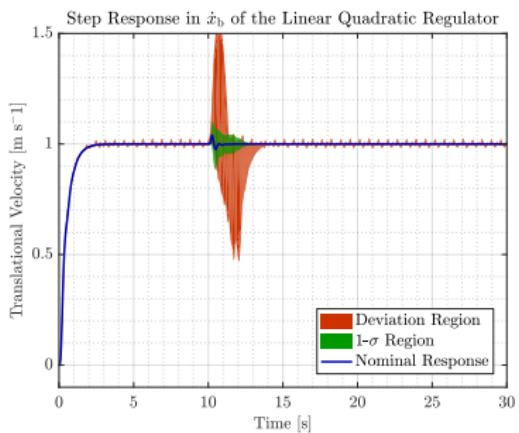


Simulation of LQR and robust design

- ▶ Disturbances from wind and waves
 - ▶ ± 1.5 N along \dot{x}_b
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 - ▶ The frequency for both varies between 0-10 Hz
- ▶ The parameters are varied $\pm 20\%$
 - ▶ Mass, m
 - ▶ Moment of inertia, I_z , around z_b
 - ▶ The damping coefficients d_x and d_y
 - ▶ The lengths l_1 and l_2
- ▶ Monte Carlo simulations with 1000 realizations

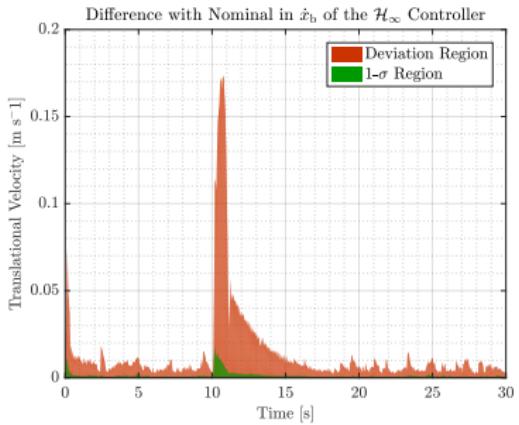
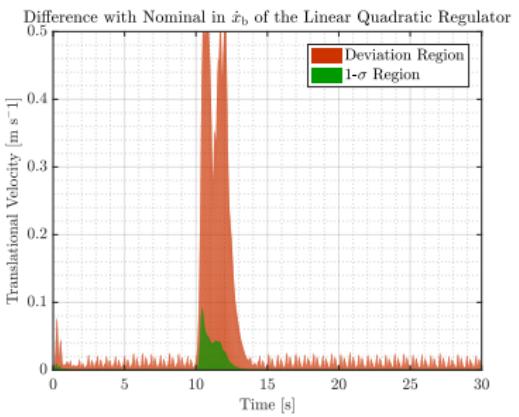
Inner Controller

Comparison of the Controllers



Inner Controller

Comparison of the Controllers

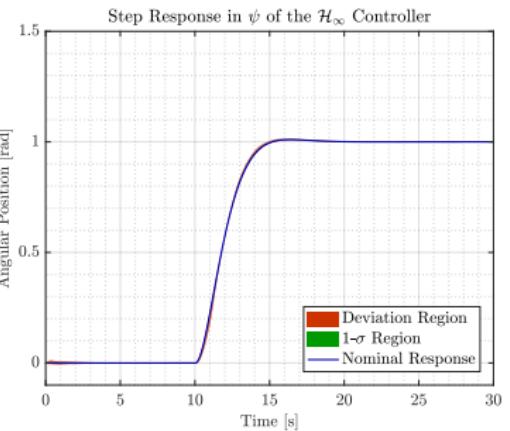
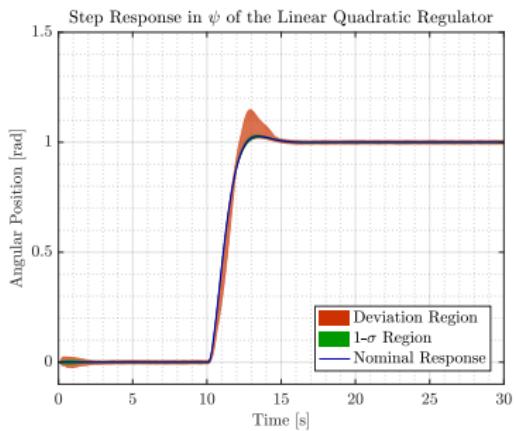


Inner Controller

Comparison of the Controllers

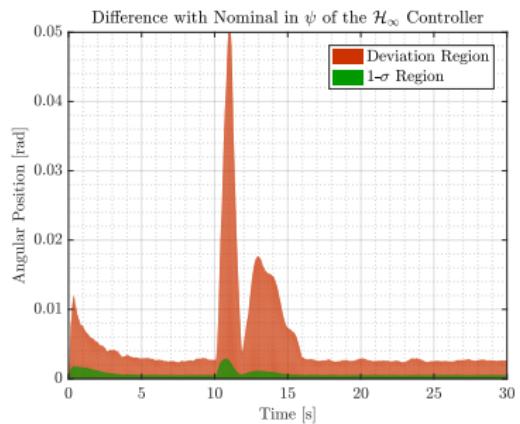
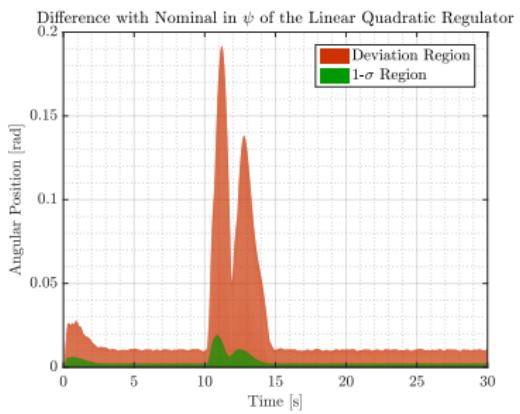


39



Inner Controller

Comparison of the Controllers



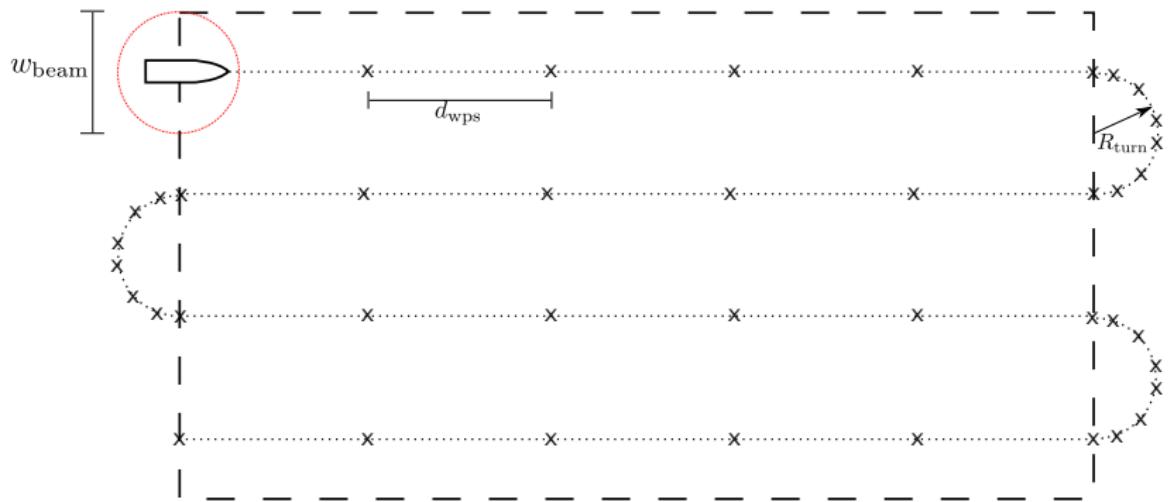
Agenda



- ▶ Introduction
- ▶ System Description
- ▶ Model
- ▶ Control Approach
- ▶ Sensor Fusion
- ▶ Inner Controller
- ▶ **Outer Controller**
 - Path Generation Algorithm
 - Path Following Algorithm
- ▶ **Results**
 - Controller Results
 - Implementation Results
- ▶ Conclusion

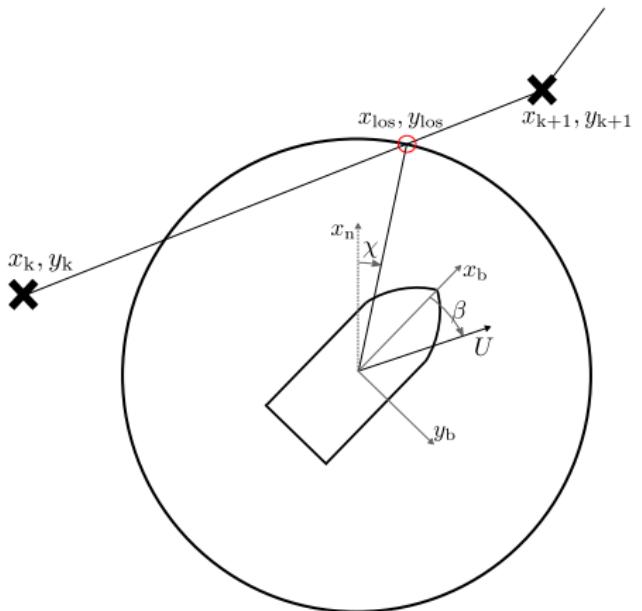
Outer Controller

Path Generation Algorithm



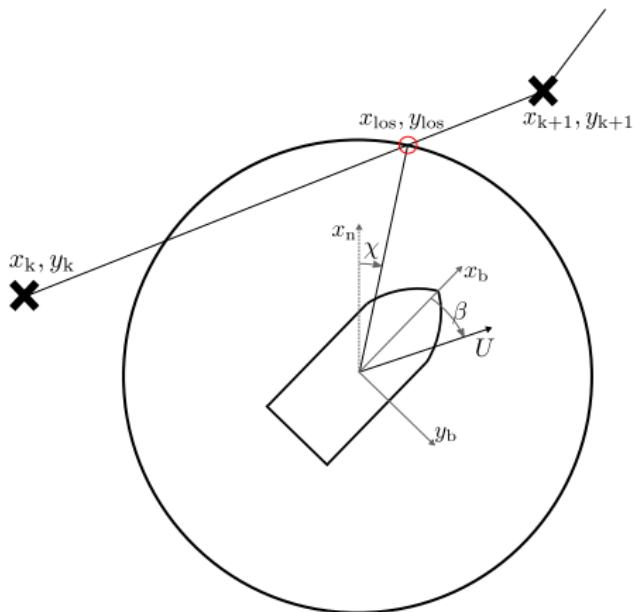
Outer Controller

Path Following Algorithm



Outer Controller

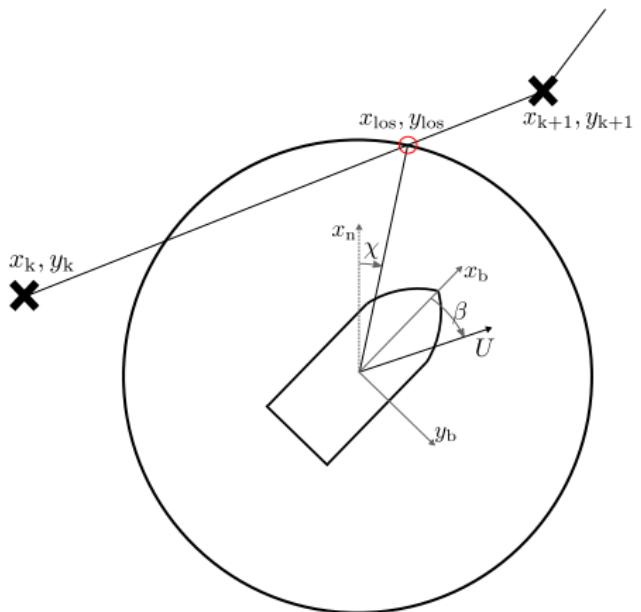
Path Following Algorithm



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

Outer Controller

Path Following Algorithm

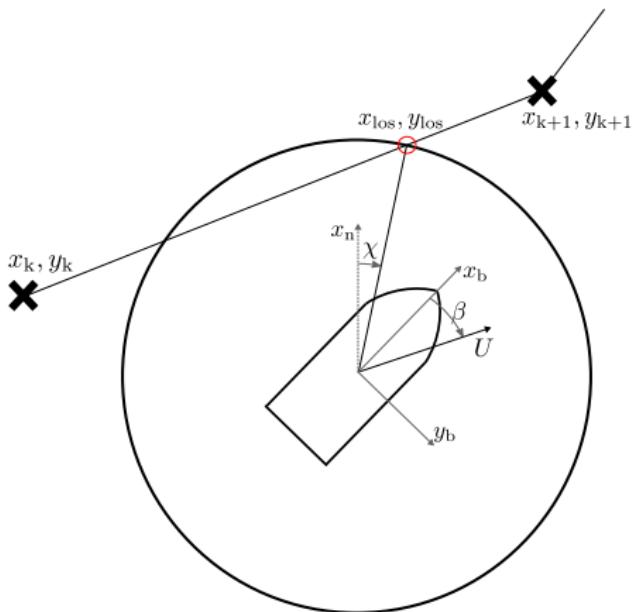


$$\chi = \arctan \left(\frac{y_{\text{LOS}} - y_n}{x_{\text{LOS}} - x_n} \right)$$

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

Outer Controller

Path Following Algorithm



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

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

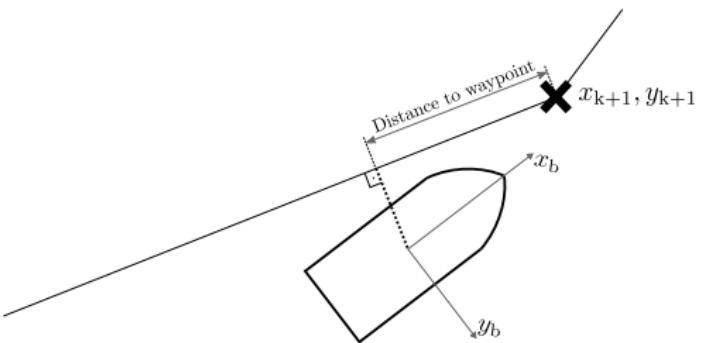
$$\psi_{\text{ref}} = \chi - \beta$$

Outer Controller

Path Following Algorithm



- ▶ Change active waypoints

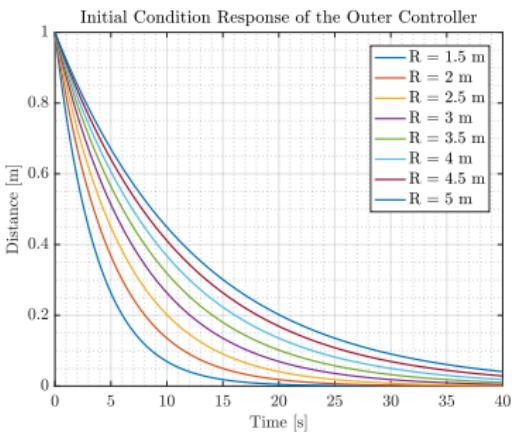
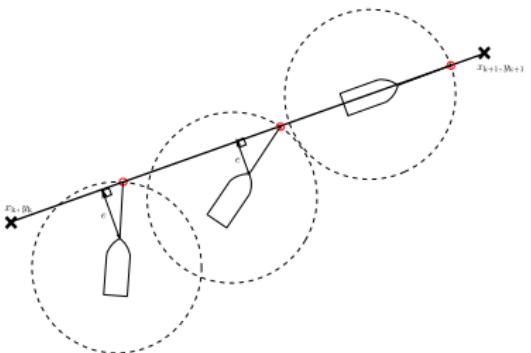


Outer Controller

Path Following Algorithm



- ▶ Convergence to the path

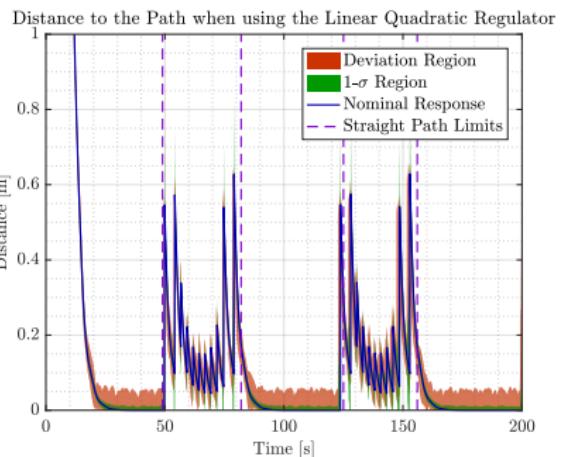
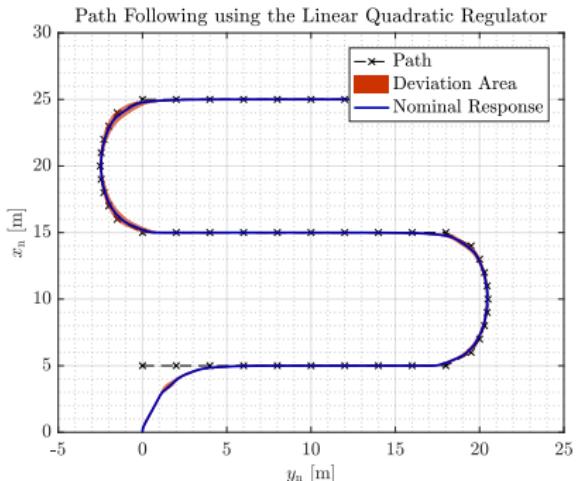


Results

Controller Results



► LQR as inner controller

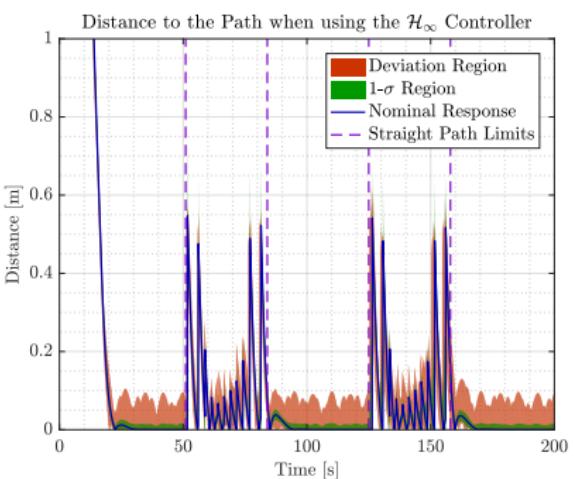
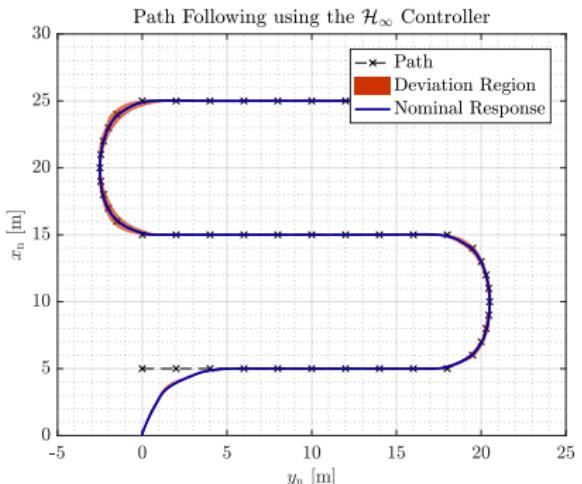


Results

Controller Results



- ▶ Robust controller as inner controller

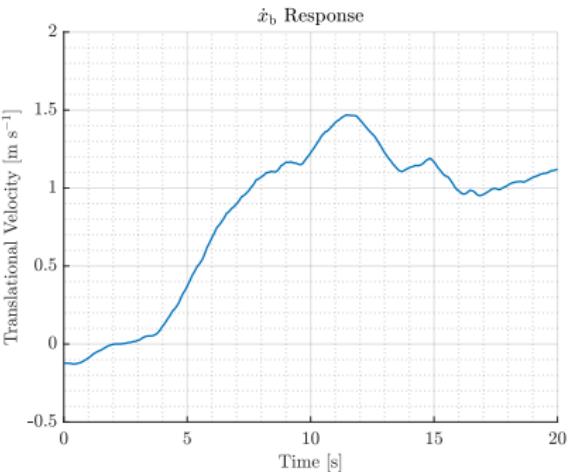
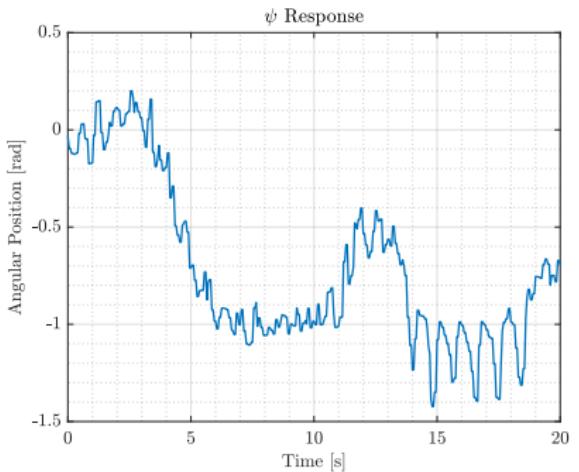


Results

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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