|  |
| --- |
| SIGHTLINE CAPSTONE PROJECT |
| STATEMENT OF WORK |
| UAV PLUG AND PLAY PRECISION LANDING AID |

|  |
| --- |
| 1-4-2019 |

**PROJECT OVERVIEW**

### **BACKGROUND**

### SightLine Applications has developed a precision visual landing algorithm that provides an excellent set of benefits:

* Works in degraded and denied GPS environments – Safety and reliability.
* Reduces operator training and landing phase complexity.
* Provides detection functions for landing zone safety - detect people, animals, or objects from entering the landing zone
* Provides a rich set of telemetry for flight controllers. 30 Hz data with range, XY offsets, relative azimuth, etc.
* Supports landing on moving platforms - ground vehicles, marine.
* Is not impacted by bright sun or low light conditions.
* Can be used with Thermal (IR) cameras as well as visible (EO) cameras
* Effective range of operation (distance to target) only limited by the size of the landing pattern used

### **PROBLEM**

Integration of the SightLine Landing Aid for end users is problematic. Often drone operators want to just “plug in” a component and fly their mission. Installing software components is acceptable, but any requirement for programming is a barrier to entry or a complete show stopper. Various cables, power, and other electrical connectivity issues are also difficult for vehicle integrators. Rugged or at least robust mechanical enclosures, easy mounting, and environmental reliability are equally important. Lastly, choice of optical system (camera) for the greatest range has cause adoption delays in that it has been a decision left to the integrator.

**PROJECT REQUIREMENTS**

* Develop a set of electrical sub-assemblies that will allow integration of Sightline Precision Landing Aid (1500 OEM + Airborne Camera + accessories) for PX4 running on Pixhawk 4 autopilot
* Design and produce a prototype enclosure for the hardware. The enclosure should be smaller than 3” x 2” x 2”
* Develop documentation and software installers to meet plug and play expectations

**PROJECT DESIGN SPECIFICATIONS**

* Use Pixhawk 4 autopilot
* Use PX4 as an open source flight control software for drones
* Use QGROUNDCONTROL as a ground control station and mission planning
* 1500 OEM and its accessories are powered using 5V output from the Pixhawk 4 kits
* Use RS-232 or 3.3V TTL to communicate between hardware and autopilot
* Use DJI Flame Wheel F450 quadcopter

**LEVEL 0 BLOCK DIAGRAMS**

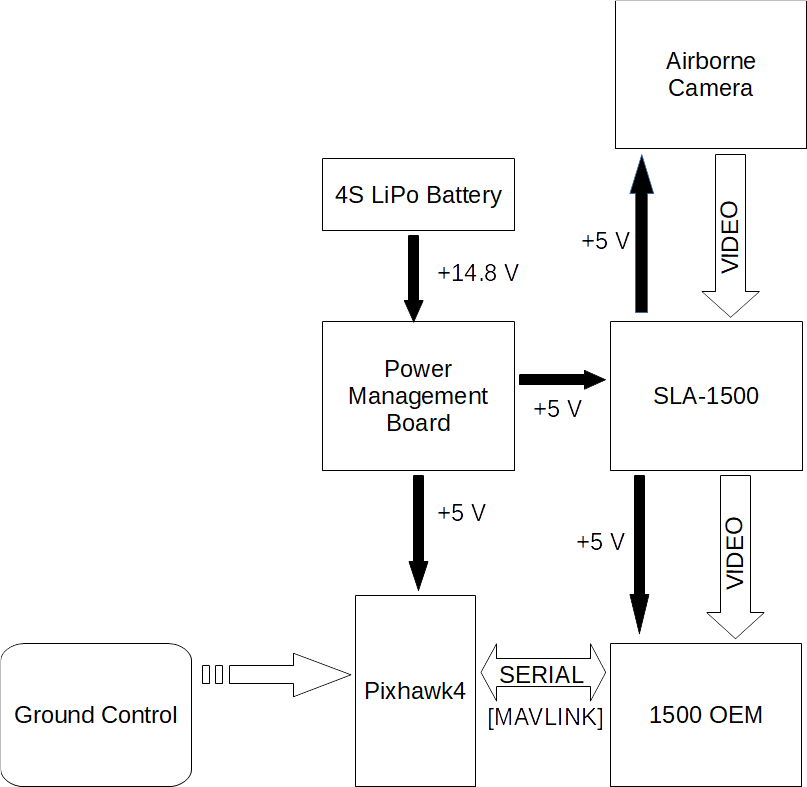


Figure 1: Level 0 diagram of current configuration

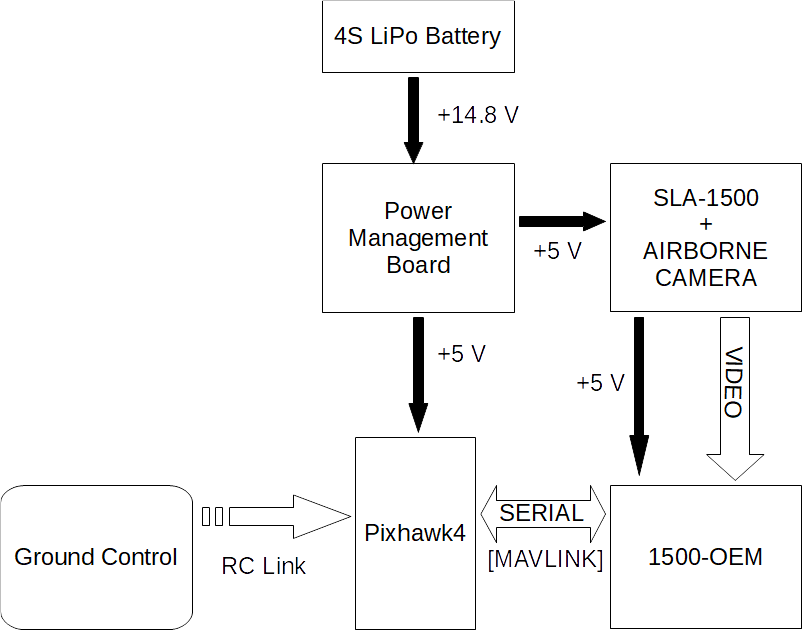


Figure 2: Level 0 diagram of desired configuration

**HARDWARE AND SOFTWARE REQUIREMENTS**

**FIRST ORDER COST ESTIMATE**

**TIMELINE**