



Accelerated Marine Vehicle Autonomy,
Sensing, and Communications


May, 2017

A Deeper Dive Into Behaviors
(Lab Discussion)

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Accelerated Marine Autonomy – “A Deeper Dive Into Behaviors”



Today's Material

From your Browser:

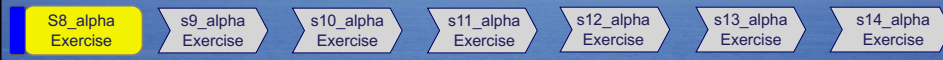
- <http://oceanai.mit.edu/ntu/lecture03.pdf>
- http://oceanai.mit.edu/ntu/lecture03_lab.pdf
- <http://oceanai.mit.edu/ntu/lab03.pdf>
- <http://oceanai.mit.edu/ntu/lecture04.pdf>
- http://oceanai.mit.edu/ntu/lecture04_lab.pdf
- <http://oceanai.mit.edu/ntu/lab04.pdf>

s8_alpha Exercise s9_alpha Exercise s10_alpha Exercise s11_alpha Exercise s12_alpha Exercise s13_alpha Exercise s14_alpha Exercise

Michael Benjamin 2017



The s8_alpha Exercise



Overview

In this lab we exercise our knowledge in:

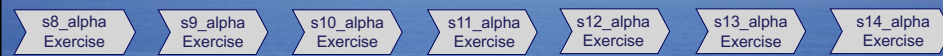
- MOOS and Helm configurations, by continuing to extend the Alpha mission
- Behavior updates parameter, Loiter, MaxDepth, ConstantDepth behaviors.

A few new topics we touch, and learn on the fly:

- Simulated drift
- IvP Helm Decision Space
- Behavior durations

Lab Exercises

- **s8_alpha**: Change the Alpha Mission to use a loiter behavior
- **s9_alpha**: Turn the vehicle into UUV, adding constant depth behavior
- **s10_alpha**: Change the vehicle depth with pMarineViewer
- **s11_alpha**: Use uTimerScript to periodically randomly choose a new depth
- **s12_alpha**: Use MaxDepth behavior to limit the maximum depth
- **s13_alpha**: Periodic surface for fixed time (GPS fix)
- **s14_alpha**: Add simulated drift to the mission



The s8_alpha Exercise



To Start: Copy the s1_alpha mission, calling it s8_alpha

- Remove the Waypoint Survey behavior and replace with a Loiter Behavior
- Loiter at Position 75,-75, with a radius of 30 meters, in an octagon



S8_alpha
Exercise

s9_alpha
Exercise

s10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

s14_alpha
Exercise

Requirements of the s8_alpha Exercise



1. Remove the Waypoint behavior
2. Add the Loiter Behavior

```
//-----
Behavior = BHV_Loiter
{
  name      = loiter
  priority  = 100
  condition = RETURN = false
  condition = DEPLOY = true
  updates   = UP_LOITER
  speed     = 1.3
  clockwise = false
  radius    = 6.0
  slip_radius = 25.0
  polygon    = format=radial, x=75, y=-75, radius=30, pts=8, snap=1
  visual_hints = nextpt_color=yellow, nextpt_lcolor=khaki
  visual_hints = edge_color=white, vertex_color=dodger_blue
  visual_hints = edge_size=1, vertex_size=3, label=LOITER_POLYGON
  visual_hints = nextpt_vertex_size=5
}
```

S8_alpha
Exercise

s9_alpha
Exercise



s10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise



s13_alpha
Exercise

s14_alpha
Exercise

The s9_alpha Exercise


s8_alpha Exercise
S9_alpha Exercise
s10_alpha Exercise
s11_alpha Exercise
s12_alpha Exercise
s13_alpha Exercise
s14_alpha Exercise





The s9_alpha Exercise

To Start: Copy the s8_alpha mission, calling it s9_alpha

- Add Depth to the mission.
- Set the Loiter depth to be 20 meters

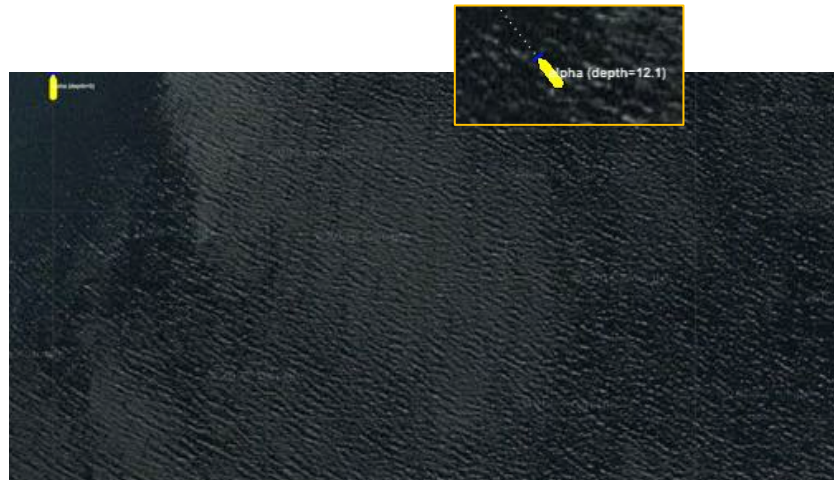




hint: toggle the vehicle label with the 'n' key, to see the depth.

s8_alpha Exercise
S9_alpha Exercise
s10_alpha Exercise
s11_alpha Exercise
s12_alpha Exercise
s13_alpha Exercise
s14_alpha Exercise

The s9_alpha Exercise



s8_alpha
Exercise

S9_alpha
Exercise

s10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

s14_alpha
Exercise

Requirements of the s9_alpha Exercise



1. Add the ConstantDepth Behavior
 2. Configure the Helm to reason about depth
 3. Configure the Simulator to reason about depth
 4. Configure the PID controller to reason about depth
-
1. Add the ConstantDepth Behavior (to the [alpha.bhv](#) file)

```
//-----
Behavior=BHV_ConstantDepth
{
  name      = const_depth
  pwt       = 100
  condition = DEPLOY = true
  duration  = no-time-limit
  updates   = DEPTH_UPDATE
  depth     = 20
}
```

← This behavior will be active
when surveying and returning

s8_alpha
Exercise

S9_alpha
Exercise

s10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

s14_alpha
Exercise

Requirements of the s9_alpha Exercise

2. Configure the Helm to reason about depth

```
//-----
// pHelmIvP configuration block
ProcessConfig = pHelmIvP
{
  AppTick      = 4
  CommsTick    = 4

  behaviors    = alpha.bhv
  domain       = course:0:359:360
  domain       = speed:0:4:41
  domain       = depth:0:100:101
}
```

Add this line:
The helm will now also consider
depths 0, 1, 2, ... 100.

像matlab上下限、區間數

s8_alpha
Exercise

S9_alpha
Exercise

s10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

s14_alpha
Exercise

Requirements of the s9_alpha Exercise

3. Configure the Simulator (uSimMarine) to reason about depth

```
//-----
// uSimMarine configuration block
ProcessConfig = uSimMarine
{
  AppTick      = 4
  CommsTick    = 4

  start_x      = 0
  start_y      = -20
  start_heading = 180
  start_speed   = 0
  prefix       = NAV
  turn_rate    = 40
  thrust_map   = 0:0, 20:1, 40:2, 60:3, 80:4, 100:5

  buoyancy_rate = 0.075
  max_depth_rate = 5
  max_depth_rate_speed = 2.0
  default_water_depth = 400
}
```

Add these lines:

s8_alpha
Exercise

S9_alpha
Exercise

s10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

s14_alpha
Exercise

Requirements of the s9_alpha Exercise

4. Configure the PID Controller (pMarinePID) to reason about depth

```
//-----
// pMarinePID configuration block
ProcessConfig = pMarinePID
{
  AppTick      = 4
  CommsTick    = 4
  . . .
  depth_control = true
  . . .
  maxpitch     = 15
  maxelevators = 13
  // Pitch PID controller
  pitch_pid_kp = 1.5
  pitch_pid_kd = 1.0
  pitch_pid_ki = 0
  pitch_pid_integral_limit = 0
  // ZPID controller
  z_to_pitch_pid_kp = 0.12
  z_to_pitch_pid_kd = 0
  z_to_pitch_pid_ki = 0.004
  z_to_pitch_pid_integral_limit = 0.05
}
```

Change from false to true

Add these lines:

s8_alpha
Exercise

S9_alpha
Exercise

s10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

s14_alpha
Exercise

The s10_alpha Exercise

s8_alpha
Exercise

s9_alpha
Exercise

S10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

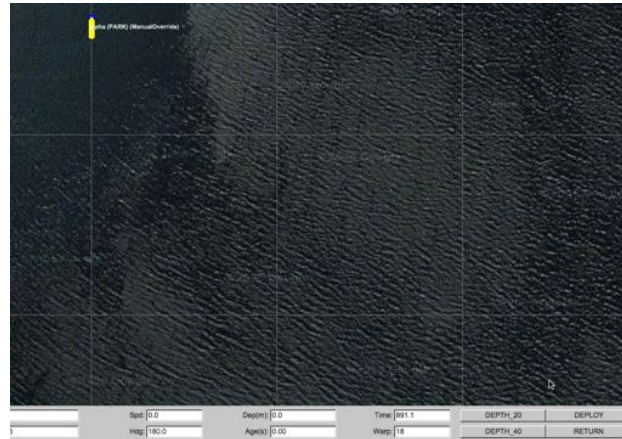
s14_alpha
Exercise

The s10_alpha Exercise



To Start: Copy the s9_alpha mission, calling it s10_alpha

- Add buttons to pMarineViewer to command depth=20 and depth=40
- Use the updates parameter for the ConstantDepth behavior



s8_alpha
Exercise

s9_alpha
Exercise

S10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

s14_alpha
Exercise

Requirements of the s10_alpha Exercise



1. Use the **updates** parameter to allow dynamic changes to the ConstantDepth behavior

```
//-----
Behavior=BHV_ConstantDepth
{
  name      = const_depth
  pwt       = 100
  condition = DEPLOY = true
  duration  = no-time-limit
  updates   = DEPTH_UPDATE
  depth     = 20
}
```

← Add this line

s8_alpha
Exercise

s9_alpha
Exercise

S10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

s14_alpha
Exercise

Requirements of the s10_alpha Exercise

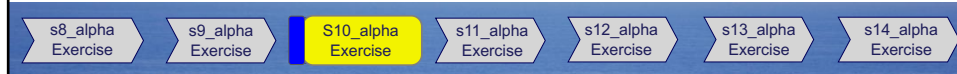
2. Configure pMarineViewer with two new command buttons

```
//-----
// pHelmIvP configuration block
ProcessConfig = pHelmIvP
{
  AppTick      = 4
  CommsTick    = 4

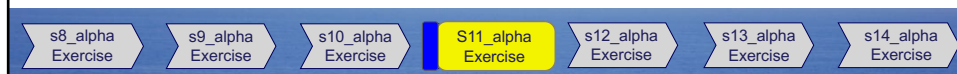
  button_three = DEPTH_20 # DEPTH_UPDATE = depth=20
  button_four  = DEPTH_40 # DEPTH_UPDATE = depth=40
}
```

← Add these two lines

Button label MOOS Variable Behavior Parameter Parameter Value



The s11_alpha Exercise



The s11_alpha Exercise



To Start: Copy the s10_alpha mission, calling it s11_alpha

- Add a Timer Script to randomly change depths every two minutes
- Choose random depths in the range 20 to 80 meters



s8_alpha
Exercise

s9_alpha
Exercise

s10_alpha
Exercise

S11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

s14_alpha
Exercise

Requirements of the s11_alpha Exercise



1. Add uTimerScript to the alpha.moos Antler configuration block

```
//-----
// Antler configuration block
ProcessConfig = ANTLER
{
  MSBetweenLaunches = 200

  Run = MOOSDB           @ NewConsole = false
  Run = pLogger           @ NewConsole = false
  Run = uSimMarine        @ NewConsole = false
  Run = pMarinePID        @ NewConsole = false
  Run = pHelmIvP          @ NewConsole = false
  Run = pMarineViewer     @ NewConsole = false
  Run = uProcessWatch     @ NewConsole = false
  Run = pNodeReporter     @ NewConsole = false
  Run = uTimerScript      @ NewConsole = false
}
```

← Add this line

s8_alpha
Exercise

s9_alpha
Exercise

s10_alpha
Exercise

S11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

s14_alpha
Exercise

Requirements of the s11_alpha Exercise



1. Add the `uTimerScript` configuration block to the `alpha.moos` file

```
//-----
// uTimerScript configuration block
ProcessConfig = uTimerScript
{
  AppTick      = 4
  CommsTick    = 4

  condition    = DEPLOY = true
  randvar      = varname=RND_DEPTH, min=20, max=80, key=at_reset
  event        = var=DEPTH_UPDATE, val=depth=${RND_DEPTH}, time=120
  reset_max    = nolimit  reset_time = all-posted
}
```

s8_alpha
Exercise

s9_alpha
Exercise

s10_alpha
Exercise

S11_alpha
Exercise

s12_alpha
Exercise

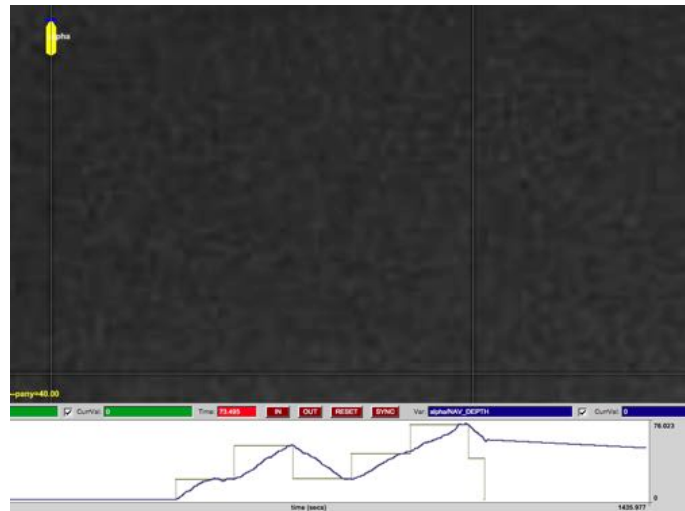
s13_alpha
Exercise

s14_alpha
Exercise

Requirements of the s11_alpha Exercise



Confirm by looking at the alog file with `alogview`



s8_alpha
Exercise

s9_alpha
Exercise


s10_alpha
Exercise

S11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

s14_alpha
Exercise

 MITRECH
Center for
Robotics
Engineering

The s12_alpha Exercise

s8_alpha
Exercise

s9_alpha
Exercise


s10_alpha
Exercise

s11_alpha
Exercise

S12_alpha
Exercise

s13_alpha
Exercise


s14_alpha
Exercise

 MITRECH
Center for
Robotics
Engineering

The s12_alpha Exercise

To Start: Copy the s11_alpha mission, calling it s12_alpha

- Add a MaxDepth behavior
- Choose random depths in the range 20 to 80 meters, but MaxDepth limits to 50m



s8_alpha
Exercise

s9_alpha
Exercise

s10_alpha
Exercise

s11_alpha
Exercise

S12_alpha
Exercise

s13_alpha
Exercise

s14_alpha
Exercise

Requirements of the s12_alpha Exercise



1. Add the MaxDepth behavior to the alpha.bhv file.

```
//-----
Behavior=BHV_MaxDepth
{
  name      = max_depth
  pwt       = 200
  condition = DEPLOY = true
  duration  = no-time-limit
  max_depth = 50
  basewidth = 0
}
```

← Priority weight higher than constant depth behavior

← No tolerance beyond max_depth

s8_alpha
Exercise

s9_alpha
Exercise

s10_alpha
Exercise

s11_alpha
Exercise

S12_alpha
Exercise

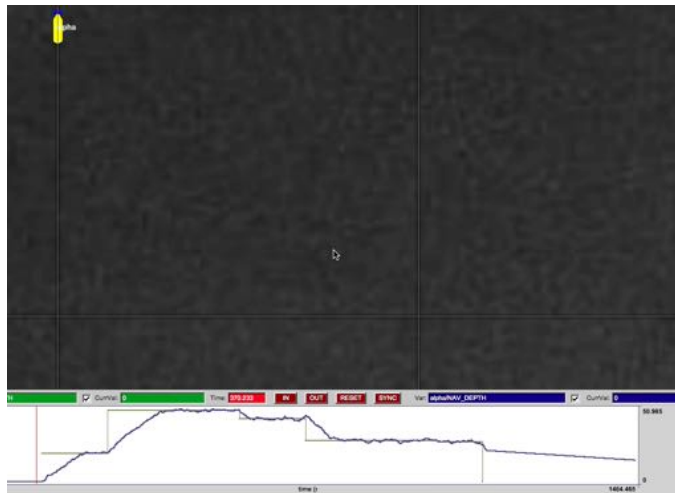
s13_alpha
Exercise

s14_alpha
Exercise

Requirements of the s12_alpha Exercise



Confirm by looking at the log file with [alogview](#)



s8_alpha
Exercise

s9_alpha
Exercise


s10_alpha
Exercise

s11_alpha
Exercise

S12_alpha
Exercise


s13_alpha
Exercise

s14_alpha
Exercise



The s13_alpha Exercise


s8_alpha Exercise
s9_alpha Exercise
s10_alpha Exercise
s11_alpha Exercise
s12_alpha Exercise
S13_alpha Exercise
s14_alpha Exercise



The s13_alpha Exercise

To Start:

- Copy the **s9_alpha** mission, calling it **s13_alpha**
- Add a Timer behavior to periodically (30 secs) turn off the depth behavior
- Float to the surface, wait at the surface for 30 secs, then resume



s8_alpha Exercise
s9_alpha Exercise
s10_alpha Exercise
s11_alpha Exercise
s12_alpha Exercise
S13_alpha Exercise
s14_alpha Exercise

Requirements of the s13_alpha Exercise



1. Add Two Timer behaviors to the alpha.bhv file.

```
//-----
Behavior=BHV_Timer
{
  name      = timer_need_gps
  condition = DEPLOY = true
  condition = NEED_GPS = false
  perpetual = true
  endflag   = NEED_GPS = true
  duration  = 300
  duration_idle_decay = false
}
```



Only running when NEED_GPS is true



Shuts off its own condition (NEED_GPS) when it completes

```
//-----
Behavior=BHV_Timer
{
  name      = timer_wait_gps
  condition = DEPLOY = true
  condition = NAV_DEPTH < 2
  condition = NEED_GPS = true
  perpetual = true
  endflag   = NEED_GPS=false
  duration  = 30
  duration_idle_decay = false
}
```



This timer starts only when at the surface



After a 30 secs at the surface it completes



Set timer to NOT decay when idle

s8_alpha
Exercise

s9_alpha
Exercise

s10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

S13_alpha
Exercise

s14_alpha
Exercise

Requirements of the s13_alpha Exercise



2. Initialize the variable indicating a need for GPS to be false

In the alpha.bhv file:

```
//-----      FILE: alpha.bhv      -----
initialize  DEPLOY  = false
initialize  RETURN  = false
initialize  NEED_GPS = false
```



Add this line

s8_alpha
Exercise

s9_alpha
Exercise

s10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

S13_alpha
Exercise

s14_alpha
Exercise

Requirements of the s13_alpha Exercise



2. Initialize the variable indicating a need for GPS to be false

In the alpha.bhv file:

```
//----- FILE: alpha.bhv -----
initialize  DEPLOY  = false
initialize  RETURN  = false
initialize  NEED_GPS = false
```

← Add this line

s8_alpha
Exercise

s9_alpha
Exercise

s10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

S13_alpha
Exercise

s14_alpha
Exercise

The s14_alpha Exercise



s8_alpha
Exercise

s9_alpha
Exercise

s10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

S14_alpha
Exercise

The s14_alpha Exercise



To Start: Copy the **s13_alpha** mission, calling it **s14_alpha**

- Add a drift vector to the simulator, accessible by buttons in pMarineViewer
- Note the performance of the UUV with effects of drift



s8_alpha
Exercise

s9_alpha
Exercise

s10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

S14_alpha
Exercise

Requirements of the s14_alpha Exercise



1. Add two buttons to pMarineViewer to turn OFF/ON the drift vector

```
button_one = DEPLOY # DEPLOY=true
button_one = MOOS_MANUAL_OVERRIDE=false # RETURN=false
button_two = RETURN # RETURN=true
```

```
button_three = DRIFT_ON # DRIFT_VECTOR = 45,0.3
button_four = DRIFT_OFF # DRIFT_VECTOR = 0,0
```

Add these lines

uSimMarine
registers for this mail

The mail is a string
"drift angle, meters/sec"

s8_alpha
Exercise

s9_alpha
Exercise



s10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

S14_alpha
Exercise



END

s8_alpha
Exercise

s9_alpha
Exercise

s10_alpha
Exercise

s11_alpha
Exercise

s12_alpha
Exercise

s13_alpha
Exercise

s14_alpha
Exercise

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