

# A Fuzzy-Logic-Based Solution to Dynamic Target Interception and Landing with a Small Multirotor Aircraft

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January 12, 2017

# Outline

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# Background

- Develop control strategy for robust, precision landing
  - Place focus on implementable control
  - Approach from hardware constraints
  - Controller will be on board the UAV
- Use vision-based sensors only for guidance
  - Independent of specialty sensors
- Target available hardware
- Caveats
  - Only consider planar motion for target

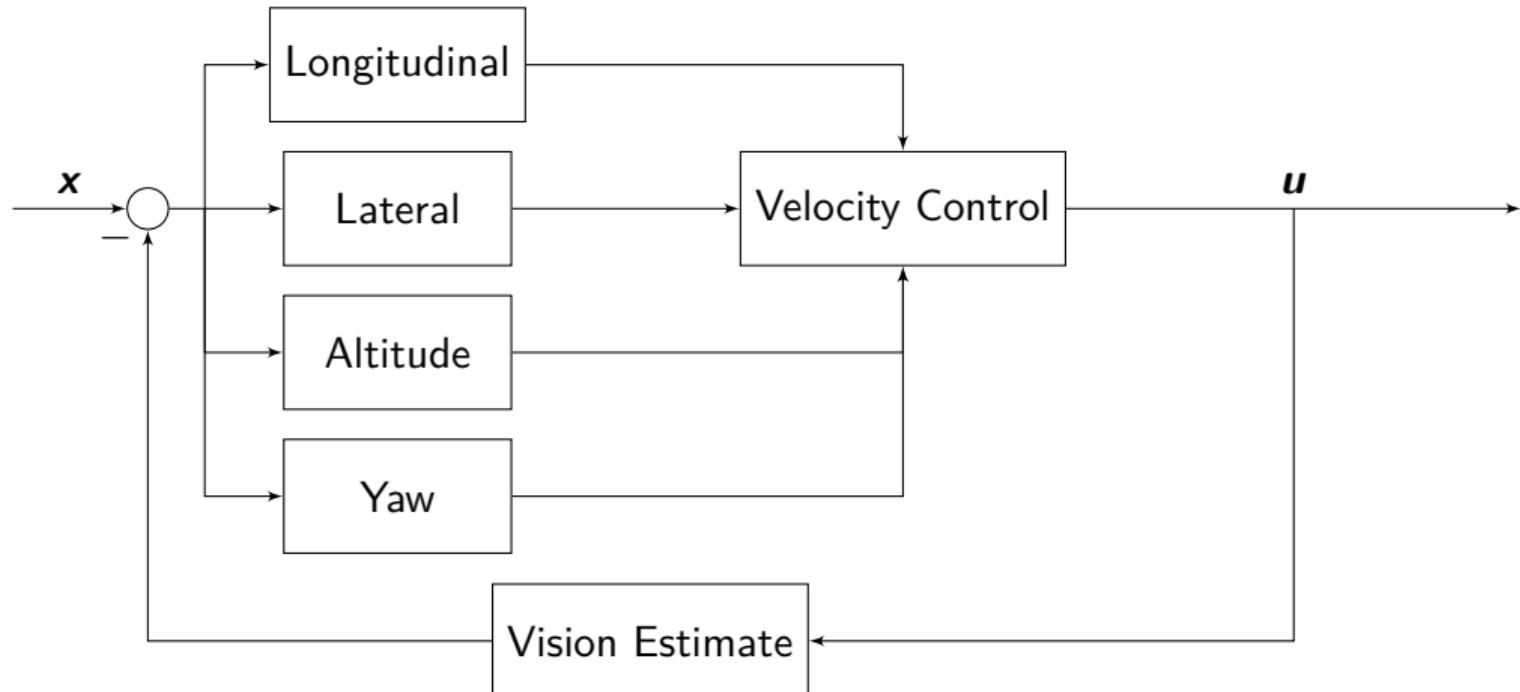
# Flight Hardware



# Motivation

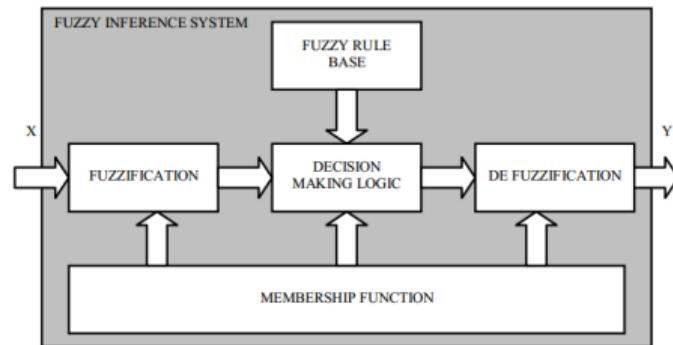
- Package delivery
- Mobile ground station deployment/recovery
- Possible on easily attainable hardware (repeatable)

# Controller



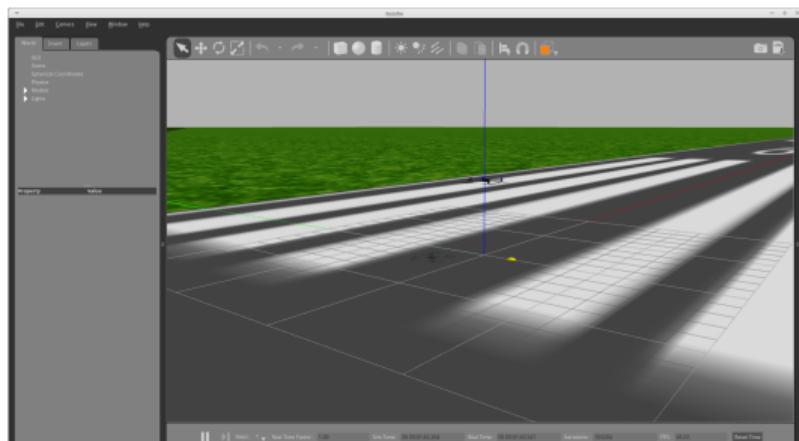
# Control

- State vector
  - $\mathbf{x} = [x, y, z, \psi]^T$
- Control
  - Input:  $\Delta x, \dot{\Delta x}$
  - Output:  $\mathbf{u} = [\dot{x}, \dot{y}, \dot{z}, \dot{\psi}]^T$
- Fuzzy Logic Controller (FLC)
  - Robust to changes in plant
  - Computationally inexpensive
  - Tolerant of noisy data



# Approach

- Simulate
  - Gazebo
  - High fidelity simulation
  - Hardware emulation
- Tune/Iterate
  - Evolutionary learning (WIP)
- Build
  - Hardware validation (WIP)



# Tools

- Robot Operating System (ROS)
  - Multithreaded, distributed framework
  - Concurrent message passing
  - Publish/Subscribe model
- Gazebo
  - 3D dynamics simulator
  - Facile sensor simulation
- AprilTags
  - Visual fiducial system for robotics
  - Developed by Univ. of Michigan
  - Robust and lightweight (small data payloads)

# Homography

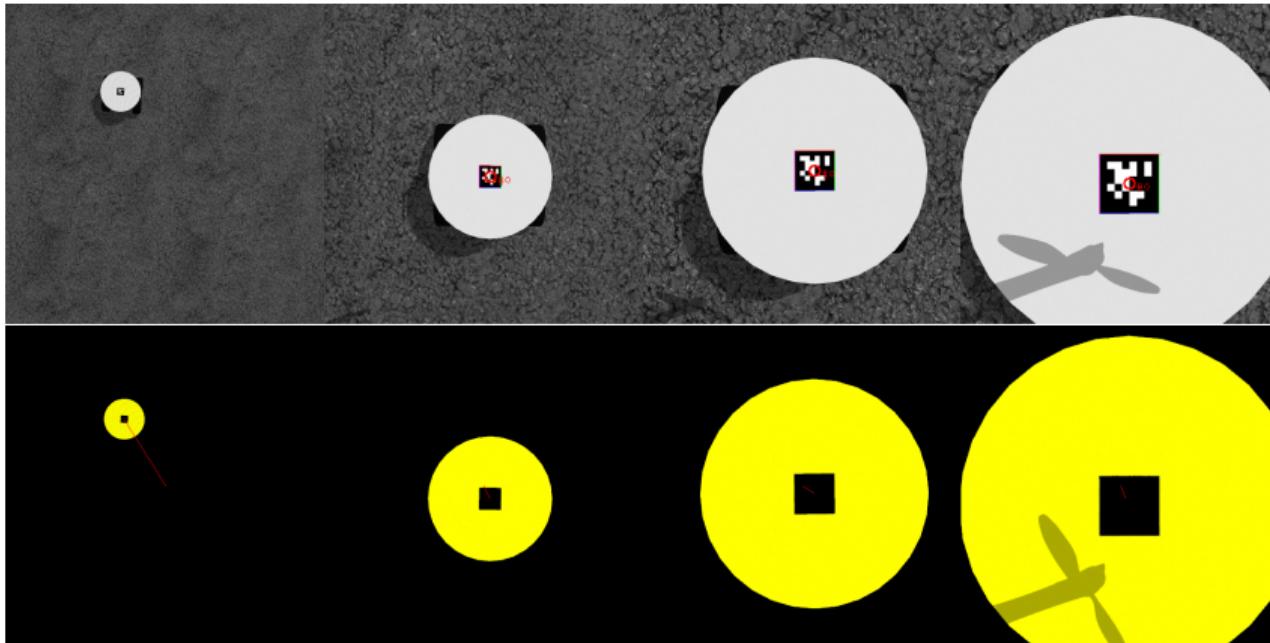
- Altitude estimation
  - Use GPS/Barometer until target is visible
  - Estimate altitude from known size of target
    - Circular Area (px) → Diameter (px) →  $\frac{d \cdot f}{m \cdot d_p} \rightarrow d_z$
  - Use AprilTag detection if available
    - Needed for target occlusion, frame saturation
- Position (2D) estimation
  - Centroid of target area
  - AprilTag if available
- Currently no fusion estimate implemented (WIP)

# AprilTags

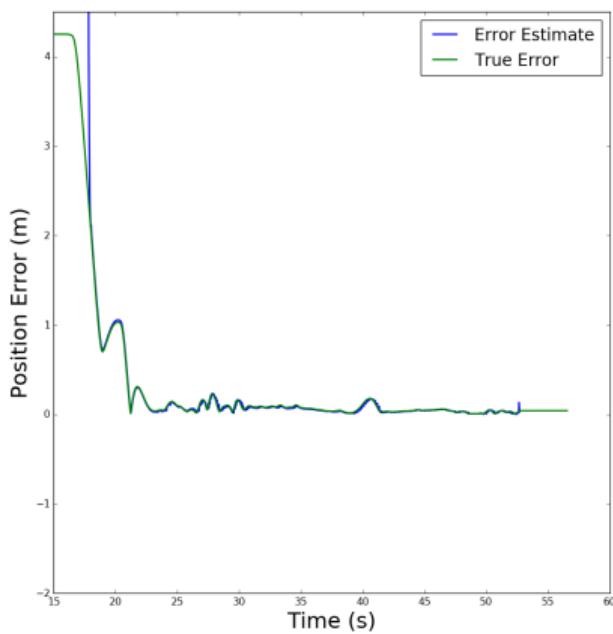
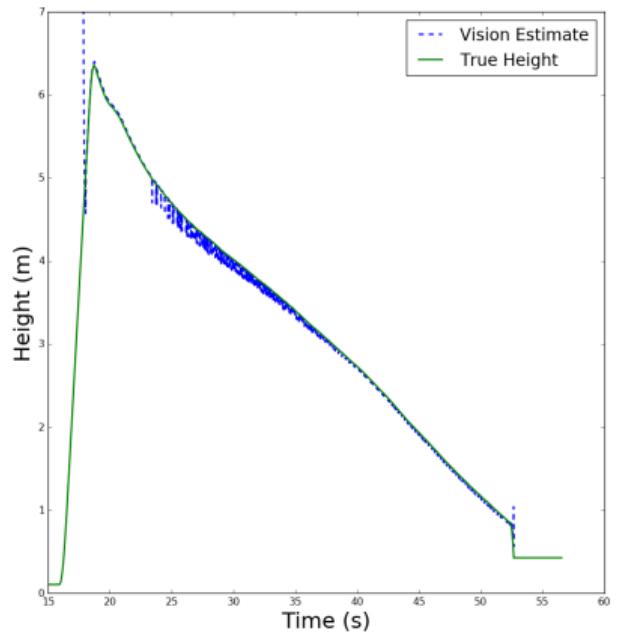
- Position
  - $x = 0$
  - $y = 0$
  - $z = 514$
- Orientation
  - $x = 0.925$
  - $y = -0.370$
  - $z = -0.024$
  - $w = 0.078$



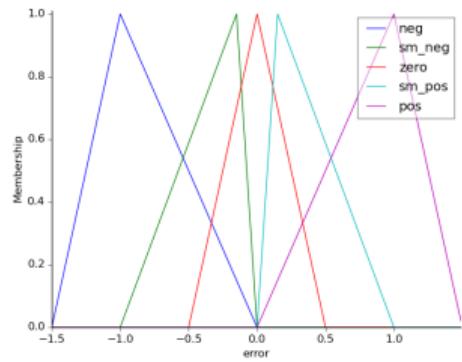
## Pose Estimation (1/2)



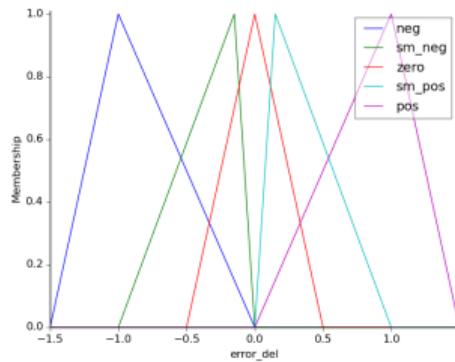
## Pose Estimation (2/2)



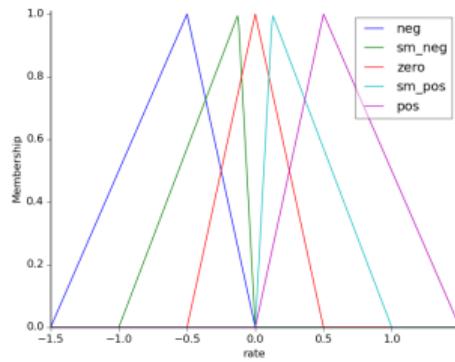
# Membership Functions



Error input template



Error change input template



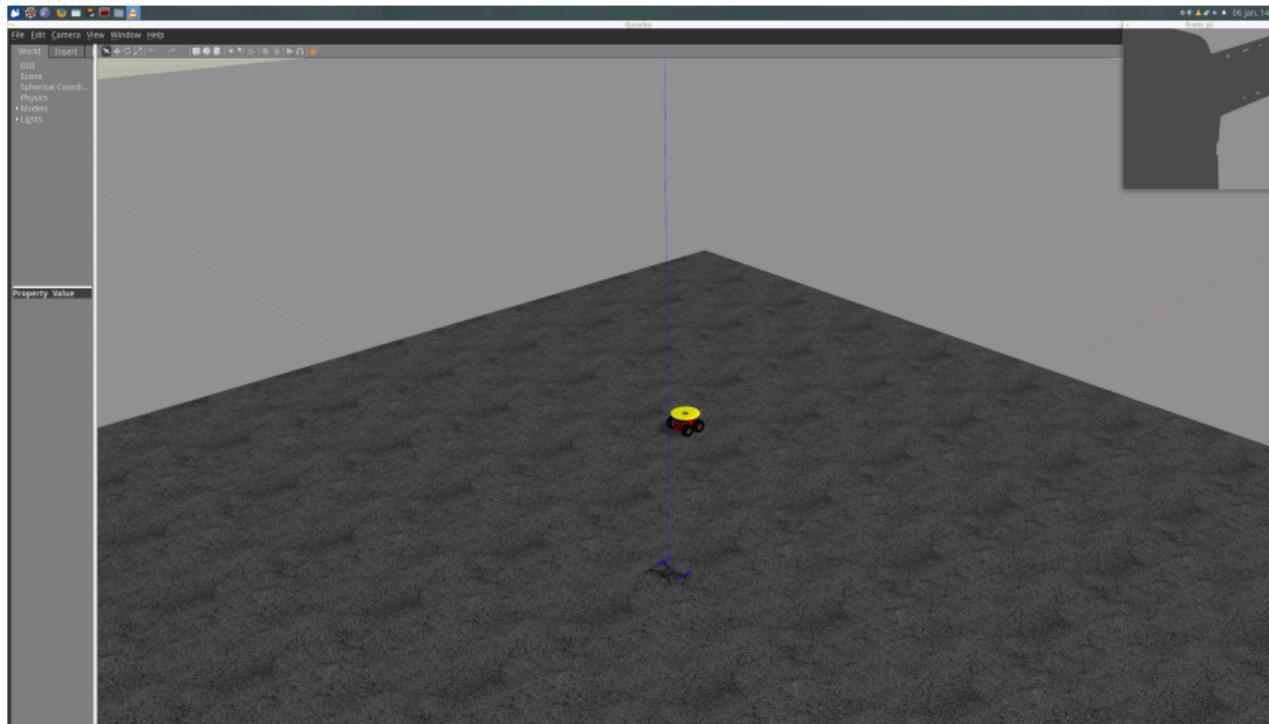
Velocity output template

## Rule Base

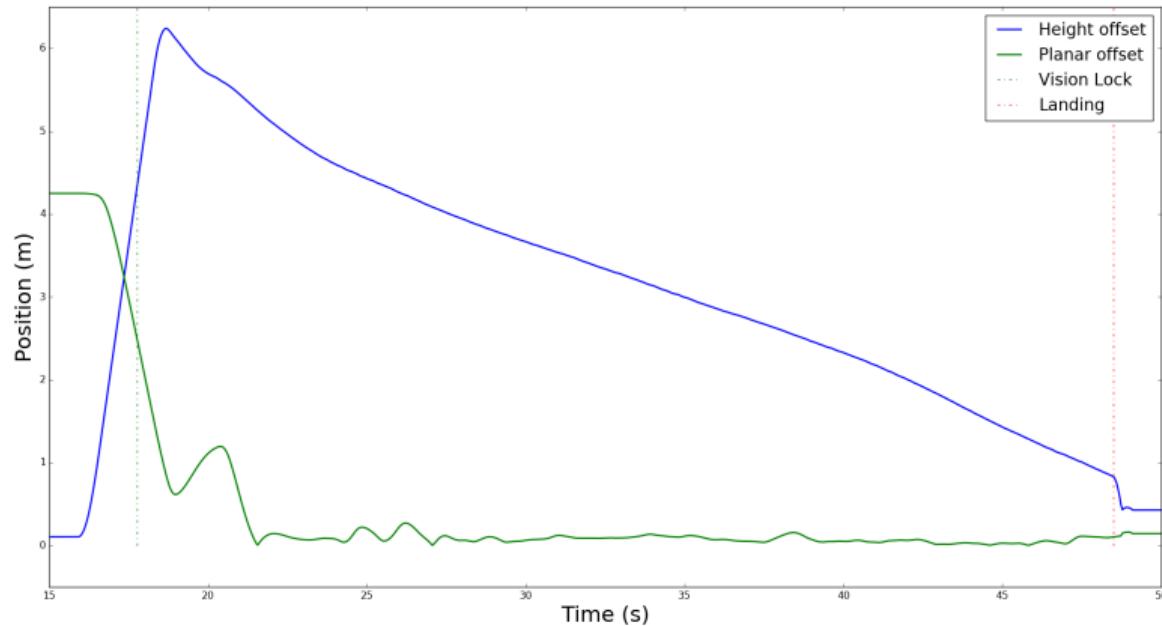
Fuzzy rule base

		error					
		N	SN	Z	SP	P	
error rate		N	P	P	SP	SP	Z
		SN	P	SP	SP	Z	SN
		Z	SP	SP	Z	SN	SN
		SP	SP	Z	SN	SN	N
		P	Z	SN	SN	N	N

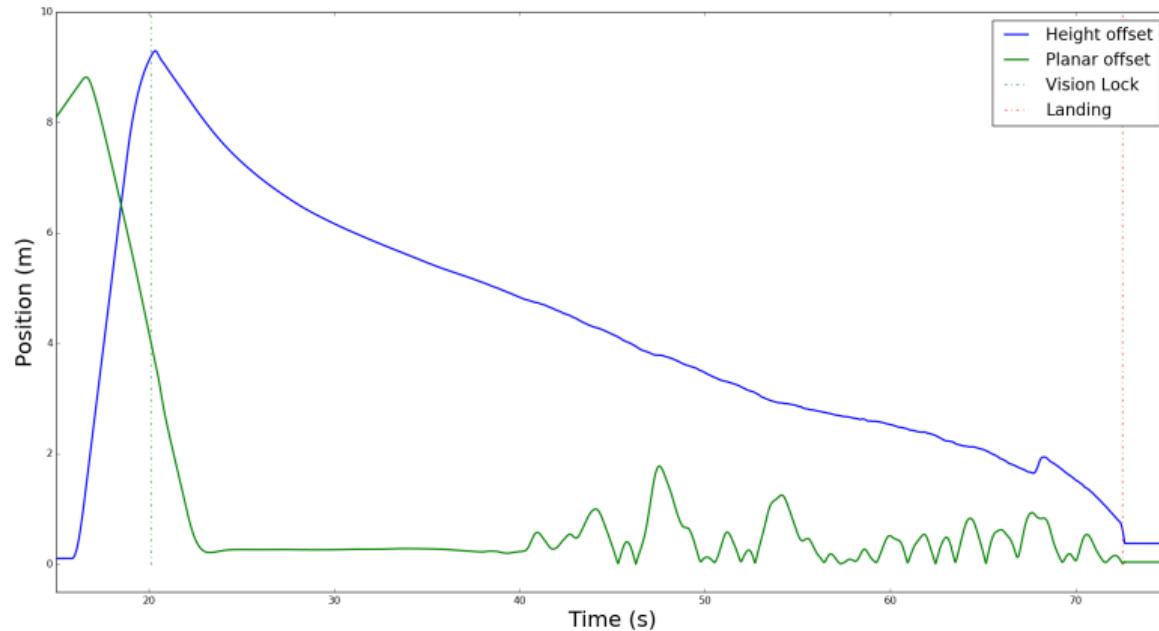
# Simulation



# Static Target



# Dynamic Target



# Conclusions

- Untuned FLC
- Noisy data
- Drastically different plants
- FLC is still able to handle it (albeit with some trouble)
- Tested PID controller - needed different set of gains for each case

## Continuing work

- Vision estimate Kalman filter (barometer, naive estimate, AprilTag)
- Rigidly mount camera to frame
  - Current work assumes perfect gimbal
- Tune FLC (genetic algorithm)
- Test implementation on flight hardware

Questions?

