

Auv Control Code

AUVSI '97 Proceedings Association for Unmanned Vehicle Systems International.1997

Underwater Robots Junku Yuh,Tamaki Ura,George A. Bekey.2012-12-06 All life came from sea but all robots were born on land. The vast majority of both industrial and mobile robots operate on land, since the technology to allow them to operate in and under the ocean has only become available in recent years. A number of complex issues due to the unstructured, hazardous undersea environment, makes it difficult to travel in the ocean while today's technologies allow humans to land on the moon and robots to travel to Mars . . Clearly, the obstacles to allowing robots to operate in a saline, aqueous, and pressurized environment are formidable. Mobile robots operating on land work under nearly constant atmospheric pressure; their legs (or wheels or tracks) can operate on a firm footing; their bearings are not subjected to moisture and corrosion; they can use simple visual sensing and be observed by their creators working in simple environments. In contrast, consider the environment where undersea robots must operate. The pressure they are subjected to can be enormous, thus requiring extremely rugged designs. The deep oceans range between 19,000 to 36,000 ft. At a mere 33-foot depth, the pressure will be twice the normal one atmosphere pressure of 29.4 psi. The chemical environment of the sea is highly corrosive, thus requiring the use of special materials. Lubrication of moving parts in water is also difficult, and may require special sealed, waterproof joints.

Springer Handbook of Ocean Engineering Manhar R. Dhanak,Nikolaos I. Xiros.2016-07-23 This handbook is the definitive reference for the interdisciplinary field that is ocean engineering. It integrates the coverage of fundamental and applied material and encompasses a diverse spectrum of systems, concepts and operations in the maritime environment, as well as providing a comprehensive update on contemporary, leading-edge ocean technologies. Coverage includes an overview on the fundamentals of ocean science, ocean signals and instrumentation, coastal structures, developments in ocean energy technologies and ocean vehicles and automation. It aims at practitioners in a range of offshore industries and naval establishments as well as academic researchers and graduate students in ocean, coastal, offshore and marine engineering and naval architecture. The Springer Handbook of Ocean Engineering is organized in five parts: Part A: Fundamentals, Part B: Autonomous Ocean Vehicles, Subsystems and Control, Part C: Coastal Design, Part D: Offshore Technologies, Part E: Energy Conversion

Underwater Robots Gianluca Antonelli.2013-11-22 This book, now at the third edition, addresses the main control aspects in underwater manipulation tasks. The mathematical model with significant impact on the control strategy is discussed. The problem of controlling a 6-degrees-of-freedom autonomous underwater vehicle is deeply investigated and a survey of fault detection/tolerant strategies for unmanned underwater vehicles is provided. Inverse kinematics, dynamic and interaction control for underwater vehicle-manipulator systems are then discussed. The code used to generate most of the numerical simulations is made available and briefly discussed.

[Advances in Engineering Research and Application](#) Duy Cuong Nguyen,Ngoc Pi Vu,Banh Tien Long,Horst Puta,Kai-Uwe Sattler.2022-12-01 The International Conference on Engineering Research and Applications (ICERA 2022), held on December 1-2, 2022, at Thai Nguyen University of Technology in Thai Nguyen, Vietnam, provided an international forum to disseminate information on latest theories and practices in engineering research and applications. The conference focused on original research work in areas including mechanical engineering, materials and mechanics of materials, mechatronics and micro mechatronics, automotive engineering, electrical and electronics engineering, information and communication

technology. By disseminating the latest advances in the field, the Proceedings of ICERA 2022, Advances in Engineering Research and Application, assists academics and professionals alike to reshape their thinking on sustainable development.

Autonomous Underwater Vehicles Sabiha Wadoo,Pushkin Kachroo.2017-12-19 Underwater vehicles present some difficult and very particular control system design problems. These are often the result of nonlinear dynamics and uncertain models, as well as the presence of sometimes unforeseeable environmental disturbances that are difficult to measure or estimate. *Autonomous Underwater Vehicles: Modeling, Control Design, and Simulation* outlines a novel approach to help readers develop models to simulate feedback controllers for motion planning and design. The book combines useful information on both kinematic and dynamic nonlinear feedback control models, providing simulation results and other essential information, giving readers a truly unique and all-encompassing new perspective on design. Includes MATLAB® Simulations to Illustrate Concepts and Enhance Understanding Starting with an introductory overview, the book offers examples of underwater vehicle construction, exploring kinematic fundamentals, problem formulation, and controllability, among other key topics. Particularly valuable to researchers is the book's detailed coverage of mathematical analysis as it applies to controllability, motion planning, feedback, modeling, and other concepts involved in nonlinear control design. Throughout, the authors reinforce the implicit goal in underwater vehicle design—to stabilize and make the vehicle follow a trajectory precisely. Fundamentally nonlinear in nature, the dynamics of AUVs present a difficult control system design problem which cannot be easily accommodated by traditional linear design methodologies. The results presented here can be extended to obtain advanced control strategies and design schemes not only for autonomous underwater vehicles but also for other similar problems in the area of nonlinear control.

Merging Virtual and Real Execution Level Control Software for the Phoenix Autonomous Underwater Vehicle Michael L. Burns.1996-09-01 The Naval Postgraduate School (NPS) is developing an AUV, Phoenix. The Phoenix has the capability of precise navigation, however too much time is needed to validate a new section of code. NPS is also developing a virtual AUV, which has the capability of being networked, having flexible missions, and having a quick feedback of results when validating new portions of code. The virtual AUV has a drawback of never being tested for real world precision. This thesis discusses the steps taken to combine these two sets of control code to obtain the maximum functionality that will drive either the virtual or actual AUV and produce a faster feedback response to newly developed code. As a result of this effort, the newly developed control code has successfully driven both the actual and virtual AUVs and provides a means for readily validating new code. Also this new control code has given the AUV research group the ability to perform distributed software development, test all AUV hardware from either the onboard or offboard computers, conduct flexible missions, and test missions in the virtual world prior to conducting them with the AUV.

The Ocean Engineering Handbook Ferial El-Hawary.2000-12-28 Compiled with the help of an internationally acclaimed panel of experts, the Ocean Engineering Handbook is the most complete reference available for professionals. It offers you comprehensive coverage of important areas of the theory and practice of oceanic/coastal engineering and technology. This well organized text includes five major sections: M

Proceedings of the 1992 Symposium on Autonomous Underwater Vehicle Technology, June 2 and 3, 1992, Washington, DC, USA Oceanic Engineering Society (U.S.).1992

Autonomous Underwater Vehicles Frank Ehlers.2020-08-26 This book gives a state-of-the-art overview of the hot topic of autonomous underwater vehicle (AUV) design and practice. It covers a wide range of AUV application areas such as education and research, biological and oceanographic studies, surveillance purposes, military and security applications and industrial underwater applications.

Proceedings of the Technology and the Mine Problem Symposium Albert M. Bottoms,Barbara Honegger.1996

Engineering Applications for New Materials and Technologies Andreas Öchsner.2018-01-25 This book discusses the expertise, skills, and techniques

needed for the development of new materials and technologies. It focuses on finite element and finite volume methods that are used for engineering simulations, and present many state-of-the-art applications and advances to highlight these methods' importance. For example, modern joining technologies can be used to fabricate new compound or composite materials, even those formed from dissimilar component materials. These composite materials are often exposed to harsh environments, must deliver specific characteristics, and are primarily used in automotive and marine technologies, i.e., ships, amphibious vehicles, docks, offshore structures, and even robots. To achieve the desired material performance, computer-based engineering tools are widely used for simulation, data evaluation, and design processes.

Underwater Robots Gianluca Antonelli.2013-11-21 This book deals with the state of the art in underwater robotics experiments of dynamic control of an underwater vehicle. The author presents experimental results on motion control and fault tolerance to thrusters' faults with the autonomous vehicle ODIN. This second substantially improved and expanded edition new features are presented dealing with fault-tolerant control and coordinated control of autonomous underwater vehicles.

Behavior Trees for Mission Management of High-Altitude Pseudo-Satellites Andreas Klöckner.2016-11-01 High-altitude pseudo-satellites currently require large crews of highly trained personnel. In order for these platforms to become commercially viable, it is imperative that mission-level tasks are automated in a mission management system, while maintaining flight safety. The new method of behavior trees is investigated for this purpose and extended with proper initialization, continuous-time processing, and modular stateful tasks. The approach is implemented in the Modelica environment and evaluated in a complex mission Simulation.

Arduino I Steven F. Barrett.2022-05-31 This book is about the Arduino microcontroller and the Arduino concept. The visionary Arduino team of Massimo Banzi, David Cuartielles, Tom Igoe, Gianluca Martino, and David Mellis launched a new innovation in microcontroller hardware in 2005, the concept of open-source hardware. Their approach was to openly share details of microcontroller-based hardware design platforms to stimulate the sharing of ideas and promote innovation. This concept has been popular in the software world for many years. In June 2019, Joel Claypool and I met to plan the fourth edition of Arduino Microcontroller Processing for Everyone! Our goal has been to provide an accessible book on the rapidly changing world of Arduino for a wide variety of audiences including students of the fine arts, middle and senior high school students, engineering design students, and practicing scientists and engineers. To make the book more accessible to better serve our readers, we decided to change our approach and provide a series of smaller volumes. Each volume is written to a specific audience. This book, Arduino I: Getting Started is written for those looking for a quick tutorial on the Arduino environment, platforms, interface techniques, and applications. Arduino II will explore advanced techniques, applications, and systems design. Arduino III will explore Arduino applications in the Internet of Things (IoT). Arduino I: Getting Started covers three different Arduino products: the Arduino UNO R3 equipped with the Microchip ATmega328, the Arduino Mega 2560 equipped with the Microchip ATmega2560, and the wearable Arduino LilyPad.

Proceedings of 2013 Chinese Intelligent Automation Conference Zengqi Sun,Zhidong Deng.2013-07-10 Proceedings of the 2013 Chinese Intelligent Automation Conference presents selected research papers from the CIAC'13, held in Yangzhou, China. The topics include e.g. adaptive control, fuzzy control, neural network based control, knowledge based control, hybrid intelligent control, learning control, evolutionary mechanism based control, multi-sensor integration, failure diagnosis, and reconfigurable control. Engineers and researchers from academia, industry, and government can gain an inside view of new solutions combining ideas from multiple disciplines in the field of intelligent automation. Zengqi Sun and Zhidong Deng are professors at the Department of Computer Science, Tsinghua University, China.

The Operation of Autonomous Underwater Vehicles Chris Carleton.2000

Marine Robot Autonomy Mae L. Seto.2012-12-09 Autonomy for Marine Robots provides a timely and insightful overview of intelligent autonomy in marine robots. A brief history of this emerging field is provided, along with a discussion of the challenges unique to the underwater environment and their impact on the level of intelligent autonomy required. Topics covered at length examine advanced frameworks, path-planning, fault tolerance, machine learning, and cooperation as relevant to marine robots that need intelligent autonomy.

Proceedings of 3rd 2023 International Conference on Autonomous Unmanned Systems (3rd ICAUS 2023) Yi Qu.

Handbook of Marine Craft Hydrodynamics and Motion Control Thor I. Fossen.2021-04-16 Handbook of MARINE CRAFT HYDRODYNAMICS AND MOTION CONTROL The latest tools for analysis and design of advanced GNC systems Handbook of Marine Craft Hydrodynamics and Motion Control is an extensive study of the latest research in hydrodynamics, guidance, navigation, and control systems for marine craft. The text establishes how the implementation of mathematical models and modern control theory can be used for simulation and verification of control systems, decision-support systems, and situational awareness systems. Coverage includes hydrodynamic models for marine craft, models for wind, waves and ocean currents, dynamics and stability of marine craft, advanced guidance principles, sensor fusion, and inertial navigation. This important book includes the latest tools for analysis and design of advanced GNC systems and presents new material on unmanned underwater vehicles, surface craft, and autonomous vehicles. References and examples are included to enable engineers to analyze existing projects before making their own designs, as well as MATLAB scripts for hands-on software development and testing. Highlights of this Second Edition include: Topical case studies and worked examples demonstrating how you can apply modeling and control design techniques to your own designs A Github repository with MATLAB scripts (MSS toolbox) compatible with the latest software releases from Mathworks New content on mathematical modeling, including models for ships and underwater vehicles, hydrostatics, and control forces and moments New methods for guidance and navigation, including line-of-sight (LOS) guidance laws for path following, sensory systems, model-based navigation systems, and inertial navigation systems This fully revised Second Edition includes innovative research in hydrodynamics and GNC systems for marine craft, from ships to autonomous vehicles operating on the surface and under water. Handbook of Marine Craft Hydrodynamics and Motion Control is a must-have for students and engineers working with unmanned systems, field robots, autonomous vehicles, and ships. MSS toolbox: <https://github.com/cybergalactic/mss> Lecture notes: <https://www.fossen.biz/wiley> Author's home page: <https://www.fossen.biz>

Error-Correcting Codes, Finite Geometries and Cryptography Aiden A. Bruen,David L. Wehlau.2010-09-03 This interdisciplinary volume contains papers from both a conference and special session on Error-Control Codes, Information Theory and Applied Cryptography. The conference was held at the Fields Institute in Toronto, On, Canada from December 5-6, 2007, and the special session was held at the Canadian Mathematical Society's winter meeting in London, ON, Canada from December 8-10, 2007. The volume features cutting-edge theoretical results on the Reed-Muller and Reed-Solomon codes, classical linear codes, codes from nets and block designs, LDPC codes, perfect quantum and orthogonal codes, iterative decoding, magnetic storage and digital memory devices, and MIMO channels. There are new contributions on privacy reconciliation, resilient functions, cryptographic hash functions, and new work on quantum coins. Related original work in finite geometries concerns two-weight codes coming from partial spreads, $(0, 1)$ matrices with forbidden configurations, Andre embeddings, and representations of projective spaces in affine planes. Great care has been taken to ensure that high expository standards are met by the papers in this volume. Accordingly, the papers are written in a user-friendly format. The hope is that this volume will be of interest and of benefit both to the experienced and to newcomers alike.

Leveraging Applications of Formal Methods, Verification and Validation. Software Engineering Tiziana Margaria,Bernhard Steffen.2022-10-19 This four-volume set LNCS 13701-13704 constitutes contributions of the associated events held at the 11th International Symposium on Leveraging

Applications of Formal Methods, ISoLA 2022, which took place in Rhodes, Greece, in October/November 2022. The contributions in the four-volume set are organized according to the following topical sections: specify this - bridging gaps between program specification paradigms; x-by-construction meets runtime verification; verification and validation of concurrent and distributed heterogeneous systems; programming - what is next: the role of documentation; automated software re-engineering; DIME day; rigorous engineering of collective adaptive systems; formal methods meet machine learning; digital twin engineering; digital thread in smart manufacturing; formal methods for distributed computing in future railway systems; industrial day.

OCEANS 2016 - Shanghai .2016 Papers on ocean technology, exhibits from ocean equipment and service suppliers, student posters and student poster competition, tutorial on ocean technology, workshops and town hall meetings on policy and governmental process.

Intelligent Sustainable Systems Jennifer S. Raj, Yong Shi, Danilo Pelusi, Valentina Emilia Balas. 2022-08-22 This book features research papers presented at the 5th International Conference on Intelligent Sustainable Systems (ICISS 2022), held at SCAD College of Engineering and Technology, Tirunelveli, Tamil Nadu, India, during February 17-18, 2022. The book discusses latest research works that discuss the tools, methodologies, practices, and applications of sustainable systems and computational intelligence methodologies. The book is beneficial for readers from both academia and industry.

Real-Time Programming 1992 J.A. De La Puente, L. Boullart. 2017-02-21 The 47 papers in this volume provide a useful reference tool for the state-of-the-art research in real-time programming.

Advances in Robot Design and Intelligent Control Aleksandar Rodić, Theodor Borangiu. 2016-11-26 This book presents the proceedings of the 25th International Conference on Robotics in Alpe-Adria-Danube Region, RAAD 2016 held in Belgrade, Serbia, on June 30th-July 2nd, 2016. In keeping with the tradition of the event, RAAD 2016 covered all the important areas of research and innovation in new robot designs and intelligent robot control, with papers including Intelligent robot motion control; Robot vision and sensory processing; Novel design of robot manipulators and grippers; Robot applications in manufacturing and services; Autonomous systems, humanoid and walking robots; Human-robot interaction and collaboration; Cognitive robots and emotional intelligence; Medical, human-assistive robots and prosthetic design; Robots in construction and arts, and Evolution, education, legal and social issues of robotics. For the first time in RAAD history, the themes cloud robots, legal and ethical issues in robotics as well as robots in arts were included in the technical program. The book is a valuable resource for researchers in fields of robotics, engineers who implement robotic solutions in manufacturing, services and healthcare, and master's and Ph.D. students working on robotics projects.

Government Reports Announcements & Index .1994

Oceans 2005, Europe .2005

Simulation, Modeling, and Programming for Autonomous Robots Davide Brugali, Jan Broenink, Torsten Kroeger, Bruce MacDonald. 2014-09-19 This book constitutes the refereed proceedings of the 4th International Conference on Simulation, Modeling, and Programming for Autonomous Robots, SIMPAR 2014, held in Bergamo, Italy, in October 2014. The 49 revised full papers presented were carefully reviewed and selected from 62 submissions. The papers are organized in topical sections on simulation, modeling, programming, architectures, methods and tools, and systems and applications.

Distributed Autonomous Robotic Systems M. Ani Hsieh, Gregory Chirikjian. 2014-06-07 Distributed robotics is a rapidly growing and maturing interdisciplinary research area lying at the intersection of computer science, network science, control theory, and electrical and mechanical engineering. The goal of the Symposium on Distributed Autonomous Robotic Systems (DARS) is to exchange and stimulate research ideas to realize

advanced distributed robotic systems. This volume of proceedings includes 31 original contributions presented at the 2012 International Symposium on Distributed Autonomous Robotic Systems (DARS 2012) held in November 2012 at the Johns Hopkins University in Baltimore, MD USA. The selected papers in this volume are authored by leading researchers from Asia, Europe, and the Americas, thereby providing a broad coverage and perspective of the state-of-the-art technologies, algorithms, system architectures, and applications in distributed robotic systems. The book is organized into five parts, representative of critical long-term and emerging research thrusts in the multi-robot community: Coordination for Perception, Coverage, and Tracking; Task Allocation and Coordination Strategies; Modular Robots and Novel Mechanisms and Sensors; Formation Control and Planning for Robot Teams; and Learning, Adaptation, and Cognition for Robot Teams.

Proceedings of the 10th National Technical Seminar on Underwater System Technology 2018 Zainah Md Zain, Hamzah Ahmad, Dwi

Pebrianti, Mahfuzah Mustafa, Nor Rul Hasma Abdullah, Rosdiyana Samad, Maziyah Mat Noh. 2019-02-08 This book presents cutting-edge research papers in the field of Underwater System Technology in Malaysia and Asia in general. The topics covered include intelligent robotics, novel sensor technologies, control algorithms, acoustic signal processing, imaging techniques, biomimetic robots, green energy sources, and underwater communication backbones and protocols. The book showcases some of the latest technologies and applications developed to facilitate local marine exploration and exploitation. It also addresses related topics concerning the Sustainable Development Goals (SDG) outlined by the United Nations.

Mission Planning and Mission Control Software for the Phoenix Autonomous Underwater Vehicle (AUV) Bradley J. Leonhardt. 1996-03-01 The Naval Postgraduate School Autonomous Underwater Vehicle (AUV), Phoenix, has a well developed lower level architecture (Execution level) while the upper, Strategic and especially the Tactical, levels need refinement. To be useful in the fleet an easier means of creating mission code for the Strategic level is required. A software architecture needed to be implemented at the Tactical level on-board Phoenix which can accommodate multi-processes, multi-languages, multiprocessors and control hard real time constraints existing at the Execution level. Phoenix also did not have a path replanning capability prior to this thesis. The approach taken is to provide Phoenix a user friendly interface for the autogeneration of human readable mission code and the creation and implementation of a Tactical level control architecture onboard Phoenix to include path replanning. The approach utilizes Rational Behavior Model (RBM) architectural design principles. This thesis focuses on the Officer of the Deck and replanning at the Tactical level, and refinement of the Captain at the Strategic level. While further testing is necessary, Phoenix is now capable of behaving as a truly autonomous vehicle. Results of this thesis show that nontechnical personnel can generate Prolog code to perform missions on-board Phoenix. Path replanning and obstacle avoidance software are also implemented. Most important this thesis demonstrates successful operation of all three levels of the RBM architecture on-board Phoenix.

Intelligent Manufacturing & Mechatronics Mohd Hasnun Arif Hassan. 2018-04-27 This book presents the proceedings of SympoSIMM 2018, the 1st edition of the Symposium on Intelligent Manufacturing and Mechatronics. With the theme of "Strengthening Innovations Towards Industry 4.0", the book comprises the studies towards the particularity of Industry 4.0's current trends. It is divided into five parts covering various scopes of manufacturing engineering and mechatronics stream, namely Intelligent Manufacturing, Robotics, Artificial Intelligence, Instrumentation, and Modelling and Simulation. It is hoped that this book will benefit the readers in embracing the new era of Industrial Revolution 4.0.

A Overview on Behaviour-based Methods for AUV Control G. N. Roberts, University of Wales College, Newport. Mechatronics Research Centre. 2000

Controller Design for an Autonomous Underwater Vehicle Brian James Decker. 2006

Quantitative Monitoring of the Underwater Environment Benoît Zerr, Luc Jaulin, Vincent Creuze, Nathalie Debese, Isabelle Quidu, Benoît

Clement, Annick Billon-Coat. 2016-06-03 This volume constitutes the results of the International Conference on Underwater Environment,

MOQESM'14, held at "Le Quartz" Conference Center in Brest, France, on October 14-15, 2014, within the framework of the 9th Sea Tech Week, International Marine Science and Technology Event. The objective of MOQESM'14 was to bring together researchers from both academia and industry, interested in marine robotics and hydrography with application to the coastal environment mapping and underwater infrastructures surveys. The common thread of the conference is the combination of technical control, perception, and localization, typically used in robotics, with the methods of mapping and bathymetry. The papers presented in this book focus on two main topics. Firstly, coastal and infrastructure mapping is addressed, focusing not only on hydrographic systems, but also on positioning systems, bathymetry, and remote sensing. The proposed methods rely on acoustic sensors such as side scan sonars, multibeam echo sounders, phase-measuring bathymetric sonars, as well as optical systems such as underwater laser scanners. Accurate underwater positioning is also addressed in the case of the use of a single acoustic beacon, and the latest advances in increasing the vertical precision of Global Navigation Satellite System (GNSS) are also presented. Most of the above mentioned works are closely related to autonomous marine vehicles. Consequently, the second part of the book describes some works concerning the methods associated with such type of vehicles. The selected papers focus on autonomous surface or underwater vehicles, detailing new approaches for localization, modeling, control, mapping, obstacle detection and avoidance, surfacing, and software development. Some of these works imply acoustics sensing as well as image processing. Set membership methods are also used in some papers. The applications of the work presented in this book concern in particular oceanography, monitoring of oil and gas infrastructures, and military field.

Advances in Unmanned Marine Vehicles G.N. Roberts,R. Sutton.2006-01-31 Unmanned marine vehicles (UMVs) include autonomous underwater vehicles, remotely operated vehicles, semi-submersibles and unmanned surface craft. Considerable importance is being placed on the design and development of such vehicles, as they provide cost-effective solutions to a number of littoral, coastal and offshore problems. This book highlights the advanced technology that is evolving to meet the challenges being posed in this exciting and growing area of research.

Naval Research Reviews .1992

Advanced Model Predictive Control for Autonomous Marine Vehicles Yang Shi,Chao Shen,Henglai Wei,Kunwu Zhang.2023-02-13 This book provides a comprehensive overview of marine control system design related to underwater robotics applications. In particular, it presents novel optimization-based model predictive control strategies to solve control problems appearing in autonomous underwater vehicle applications. These novel approaches bring unique features, such as constraint handling, prioritization between multiple design objectives, optimal control performance, and robustness against disturbances and uncertainties, into the control system design. They therefore form a more general framework to design marine control systems and can be widely applied. Advanced Model Predictive Control for Autonomous Marine Vehicles balances theoretical rigor - providing thorough analysis and developing provably-correct design conditions - and application perspectives - addressing practical system constraints and implementation issues. Starting with a fixed-point positioning problem for a single vehicle and progressing to the trajectory-tracking and path-following problem of the vehicle, and then to the coordination control of a large-scale multi-robot team, this book addresses the motion control problems, increasing their level of challenge step-by-step. At each step, related subproblems such as path planning, thrust allocation, collision avoidance, and time constraints for real-time implementation are also discussed with solutions. In each chapter of this book, compact and illustrative examples are provided to demonstrate the design and implementation procedures. As a result, this book is useful for both theoretical study and practical engineering design, and the tools provided in the book are readily applicable for real-world implementation.

Underwater Vehicle Control and Communication Systems Based on Machine Learning Techniques Tien Anh Tran,Kolla Bhanu Prakash,Subrata Chowdhury,Ivan CK Tam.2023-12-04 The development of intelligent transportation systems, especially autonomous underwater

vehicles, has become significant in marine engineering, with an aim to enhance energy efficiency management and communication systems. This book covers different aspects of optimization of autonomous underwater vehicles and their propulsion systems via machine learning techniques. It further analyses hydrodynamic characteristics including the study of experimental investigation combined with hydrodynamic characteristics backed by MATLAB® codes and simulation study results. Features: Covers utilization of machine learning techniques with a focus on marine science and ocean engineering. Details effect of the intelligent transportation system (ITS) into the sustainable environment and ecology system. Evaluates performance of particle swarm intelligence-based optimization techniques. Reviews propulsion performance of the remote-controlled vehicles based on machine learning techniques. Includes MATLAB® examples and simulation study results. This book is aimed at graduate students and researchers in marine engineering and technology, computer science, and control system engineering.

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