



# Multi Uav Cooperative Surveillance With Spatio Temporal

**Tony H. Grubestic, Jake R. Nelson**



## **Multi Uav Cooperative Surveillance With Spatio Temporal:**

**Safe Robot Navigation Among Moving and Steady Obstacles** Andrey V. Savkin, Alexey S. Matveev, Michael Hoy, Chao Wang, 2015-09-25 Safe Robot Navigation Among Moving and Steady Obstacles is the first book to focus on reactive navigation algorithms in unknown dynamic environments with moving and steady obstacles. The first three chapters provide introduction and background on sliding mode control theory, sensor models, and vehicle kinematics. Chapter 4 deals with the problem of optimal navigation in the presence of obstacles. Chapter 5 discusses the problem of reactively navigating. In Chapter 6, border patrolling algorithms are applied to a more general problem of reactively navigating. A method for guidance of a Dubins-like mobile robot is presented in Chapter 7. Chapter 8 introduces and studies a simple biologically inspired strategy for navigation of a Dubins car. Chapter 9 deals with a hard scenario where the environment of operation is cluttered with obstacles that may undergo arbitrary motions including rotations and deformations. Chapter 10 presents a novel reactive algorithm for collision-free navigation of a nonholonomic robot in unknown complex dynamic environments with moving obstacles. Chapter 11 introduces and examines a novel purely reactive algorithm to navigate a planar mobile robot in densely cluttered environments with unpredictably moving and deforming obstacles. Chapter 12 considers a multiple robot scenario. For the Control and Automation Engineer, this book offers accessible and precise development of important mathematical models and results. All the presented results have mathematically rigorous proofs. On the other hand, the Engineer in Industry can benefit by the experiments with real robots such as Pioneer robots, autonomous wheelchairs, and autonomous mobile hospital. First book on collision-free reactive robot navigation in unknown dynamic environments. Bridges the gap between mathematical model and practical algorithms. Presents implementable and computationally efficient algorithms of robot navigation. Includes mathematically rigorous proofs of their convergence. A detailed review of existing reactive navigation algorithm for obstacle avoidance. Describes fundamentals of sliding mode control. [Optimization, Learning, and Control for Interdependent Complex Networks](#) M. Hadi Amini, 2020-02-22 This book focuses on a wide range of optimization, learning, and control algorithms for interdependent complex networks and their role in smart cities, operation smart energy systems, and intelligent transportation networks. It paves the way for researchers working on optimization, learning, and control spread over the fields of computer science, operation research, electrical engineering, civil engineering, and system engineering. This book also covers optimization algorithms for large-scale problems from theoretical foundations to real-world applications, learning-based methods to enable intelligence in smart cities, and control techniques to deal with the optimal and robust operation of complex systems. It further introduces novel algorithms for data analytics in large-scale interdependent complex networks. Specifies the importance of efficient theoretical optimization and learning methods in dealing with emerging problems in the context of interdependent networks. Provides a comprehensive investigation of advanced data analytics and machine learning algorithms for large-scale complex networks. Presents basics and mathematical foundations needed to

enable efficient decision making and intelligence in interdependent complex networks M Hadi Amini is an Assistant Professor at the School of Computing and Information Sciences at Florida International University FIU He is also the founding director of Sustainability Optimization and Learning for InterDependent networks laboratory solid lab He received his Ph D and M Sc from Carnegie Mellon University in 2019 and 2015 respectively He also holds a doctoral degree in Computer Science and Technology Prior to that he received M Sc from Tarbiat Modares University in 2013 and the B Sc from Sharif University of Technology in 2011

### **Intelligent and Fuzzy Techniques in Big Data Analytics and Decision Making** Cengiz

Kahraman, Selcuk Cebi, Sezi Cevik Onar, Basar Oztaysi, A. Cagri Tolga, Irem Ucal Sari, 2019-07-05 This book includes the proceedings of the Intelligent and Fuzzy Techniques INFUS 2019 Conference held in Istanbul Turkey on July 23 25 2019 Big data analytics refers to the strategy of analyzing large volumes of data or big data gathered from a wide variety of sources including social networks videos digital images sensors and sales transaction records Big data analytics allows data scientists and various other users to evaluate large volumes of transaction data and other data sources that traditional business systems would be unable to tackle Data driven and knowledge driven approaches and techniques have been widely used in intelligent decision making and they are increasingly attracting attention due to their importance and effectiveness in addressing uncertainty and incompleteness INFUS 2019 focused on intelligent and fuzzy systems with applications in big data analytics and decision making providing an international forum that brought together those actively involved in areas of interest to data science and knowledge engineering These proceeding feature about 150 peer reviewed papers from countries such as China Iran Turkey Malaysia India USA Spain France Poland Mexico Bulgaria Algeria Pakistan Australia Lebanon and Czech Republic

### **Multi-UAV Planning and Task Allocation** Yasmina Bestaoui Sebbane, 2020-03-27

Multi robot systems are a major research topic in robotics Designing testing and deploying aerial robots in the real world is a possibility due to recent technological advances This book explores different aspects of cooperation in multiagent systems It covers the team approach as well as deterministic decision making It also presents distributed receding horizon control as well as conflict resolution artificial potentials and symbolic planning The book also covers association with limited communications as well as genetic algorithms and game theory reasoning Multiagent decision making and algorithms for optimal planning are also covered along with case studies Key features Provides a comprehensive introduction to multi robot systems planning and task allocation Explores multi robot aerial planning flight planning orienteering and coverage and deployment patrolling and foraging Includes real world case studies Treats different aspects of cooperation in multiagent systems Both scientists and practitioners in the field of robotics will find this text valuable

### **Intelligence of Things: Technologies and Applications**

Nhu-Ngoc Dao, Quang-Dung Pham, Sungrae Cho, Ngoc Thanh Nguyen, 2024-12-16 This book aims to provide state of the art knowledge in the field of Intelligence of Things to both academic and industrial readers In particular undergraduate graduate and researchers may find valuable information to drive their future research This book is considered a reference for

numerous courses such as Artificial Intelligence Internet of Things Intelligent Systems and Mobile Networks In the industrial area this book provides information on recent studies in applying AI to IoT developments which help to align and shorten R D processes to introduce new classes of intelligent IoT products *Engineering Applications of Neural Networks* Lazaros Iliadis, Ilias Maglogiannis, Efthymoulos Kyriacou, Chrisina Jayne, 2025-07-23 The two volume set CCIS 2581 and 2582 constitutes the refereed proceedings of the 26th International Conference on Engineering Applications of Neural Networks EANN 2025 held in Limassol Cyprus during June 26 29 2025 The 41 full papers included in these proceedings were carefully reviewed and selected from 101 submissions These papers demonstrate the vitality of Artificial Intelligence algorithms and approaches as well as AI applications **Intelligent Autonomy of UAVs** Yasmina Bestaoui Sebbane, 2018-03-14 *Intelligent Autonomy of UAVs Advanced Missions and Future Use* provides an approach to the formulation of the fundamental task typical to any mission and provides guidelines of how this task can be solved by different generic robotic problems As such this book aims to provide a systems engineering approach to UAV projects discovering the real problems that need to be resolved independently of the application After an introduction to the rapidly evolving field of aerial robotics the book presents topics such as autonomy mission analysis human UAV teams homogeneous and heterogeneous UAV teams and finally UAV UGV teams It then covers generic robotic problems such as orienteering and coverage The book next introduces deployment patrolling and foraging while the last part of the book tackles an important application aerial search tracking and surveillance This book is meant for both scientists and practitioners For practitioners it presents existing solutions that are categorized according to various missions surveillance and reconnaissance 3D mapping urban monitoring precision agriculture forestry disaster assessment and monitoring security industrial plant inspection etc For scientists it provides an overview of generic robotic problems such as coverage and orienteering deployment patrolling and foraging search tracking and surveillance The design and analysis of algorithms raise a unique combination of questions from many fields including robotics operational research control theory and computer science *Guidance and Control*, 2004 **Journal of Dynamic Systems, Measurement, and Control**, 2007 *International Aerospace Abstracts*, 1997 Closing the Gap Between Research and Field Applications for Multi-UAV Cooperative Missions Harn Chin Teo, 2013 The ability to fly multiple unmanned aerial vehicles UAVs in collaboration has the potential to expand the scope of feasible UAV missions and could become the backbone of future UAV missions However despite having garnered significant research interest there is no indication that systems supporting collaborative operation of multiple UAVs are close to achieving field deployment The challenge of successfully deploying a quality system is inherently complex and systems engineering offers an approach to handle the complexities Effective application of systems engineering requires both knowledge breadth and depth This thesis presents the results of a consolidation of information intended to support the conduct of systems engineering activities and describes an experiment to ascertain the sensitivities of some key operational parameters e g acquisition pointing and

tracking The experiment was conducted using Automatic Dependent Surveillance Broadcast ADS B and visual tracking equipment employing state of the art technology to understand the operating challenges and requirements of using this equipment to provide situational awareness for a UAV pilot

**Abstract** *Cooperative search for moving targets with the ability to perceive and evade using multiple UAVs* Ziyi Wang,Wencheng Zou,Sheng Li,2023-10-28 This paper focuses on the problem of regional cooperative search using multiple unmanned aerial vehicles UAVs for targets that have the ability to perceive and evade When UAVs search for moving targets in a mission area the targets can perceive the positions and flight direction of UAVs within certain limits and take corresponding evasive actions which makes the search more challenging than traditional search problems To address this problem we first define a detailed motion model for such targets and design various search information maps and their update methods to describe the environmental information based on the prediction of moving targets and the search results of UAVs We then establish a multi UAV search path planning optimization model based on the model predictive control which includes various newly designed objective functions of search benefits and costs We propose a priority encoded improved genetic algorithm with a fine adjustment mechanism to solve this model The simulation results show that the proposed method can effectively improve the cooperative search efficiency and more targets can be found at a much faster rate compared to traditional search methods

**Multi-UAV Networks** Zhihong Liu,Shihao Yan,Yirui Cong,2024-01-17 Nowadays multi UAV systems reveal great potential value in applications such as surveillance disaster rescue mapping cargo delivery etc Through coordination among multiple or even a swarm of UAVs multi UAV systems can improve mission capability survivability and flexibility Regarding the key technologies multi UAV networks are the essential building blocks in multi UAV systems which provide the foundation for information transmission and further enable team behavior This reprint presents a collection of cutting edge research in the field of UAVs showcasing advancements and innovations in the related areas The featured papers cover topics such as object detection cooperative exploration authentication schemes machine learning methods connectivity maintenance UAV deployment intelligent mining task assignment and multi UAV swarm control They explore different aspects of UAV technology highlighting novel approaches and algorithms that enhance the efficiency security and performance of UAV systems From real time object detection to decentralized exploration strategies and secure communication protocols this reprint offers valuable insights into the potential of UAVs and their applications in diverse domains It serves as a valuable resource for researchers engineers and practitioners seeking to stay at the forefront of UAV technology and leverage its capabilities to drive innovation in their respective fields

**UAV Swarm Networks: Models, Protocols, and Systems** Fei Hu,DongXiu Ou,Xin-lin Huang,2020-12-28 UAV swarm network has been used in many critical applications such as disaster recovery area surveillance weather monitoring and military communications There are many challenging R 2 college graduate students or researchers who may want to pursue some advanced research on large scale UAV swarming and networking technologies 3

government agencies that determine the future society development in this exciting field and 4 other interested readers with a strong desire to understand the challenges of designing a QoS oriented UAV network The book editors are Dr Fei Hu Professor in Electrical and Computer Engineering at University of Alabama Tuscaloosa Alabama USA Dr Xin Lin Huang Professor in Information and Communication Engineering Tongji University Shanghai China and Dr DongXiu Ou Professor in Transportation Information Institute at Tongji University Shanghai China

**Multi-UAV Path Planning and Guidance for Cooperative Hunting in a Cluttered Environment** Joshua Savio Furtado, 2018 This thesis presents a path planning and guidance algorithm for cooperative hunting by a group of multi rotor Unmanned Aerial Vehicles UAVs A group of intelligent UAVs called pursuers work together to capture a single evader The target is known to be within a certain region called the target zone Particle Swarm Optimization is used to generate near optimal safe paths for the pursuers to get from their base location to the target zone in the presence of static obstacles Once the pursuers reach the target zone Proportional Navigation guidance law is used in conjunction with the Potential Field algorithm and Rendezvous Law to simultaneously encircle the target Previous work done in the cooperative hunting problem does not address the important aspect of rendezvous Simulations as well as experimental results are shown to demonstrate the feasibility and effectiveness of this work after testing in different scenarios

**Communicating Multi-UAV System for Cooperative SLAM-based Exploration** Nesrine Mahdoui Chedly, 2018 In the aerial robotic community a growing interest for Multi Robot Systems MRS appeared in the last years This is thanks to i the technological advances such as better onboard processing capabilities and higher communication performances and ii the promising results of MRS deployment such as increased area coverage in minimum time The development of highly efficient and affordable fleet of Unmanned Aerial Vehicles UAVs and Micro Aerial Vehicles MAVs of small size has paved the way to new large scale applications that demand such System of Systems SoS features in areas like security disaster surveillance inundation monitoring search and rescue infrastructure inspection and so on Such applications require the robots to identify their environment and localize themselves These fundamental tasks can be ensured by the exploration mission In this context this thesis addresses the cooperative exploration of an unknown environment sensed by a team of UAVs with embedded vision We propose a multi robot framework where the key problem is to cooperatively choose specific regions of the environment to be simultaneously explored and mapped by each robot in an optimized manner in order to reduce exploration time and consequently energy consumption Each UAV is able to perform Simultaneous Localization And Mapping SLAM with a visual sensor as the main input sensor To explore the unknown regions the targets selected from the computed frontier points lying between free and unknown areas are assigned to robots by considering a trade off between fast exploration and getting detailed grid maps For the sake of decision making UAVs usually exchange a copy of their local map however the novelty in this work is to exchange map frontier points instead which allow to save communication bandwidth One of the most challenging points in MRS is the inter robot communication We

study this part in both topological and typological aspects We also propose some strategies to cope with communication drop out or failure Validations based on extensive simulations and testbeds are presented

**Control, Planning, and Learning for Multi-UAV Cooperative Hunting** Jacky Juan Ze Liao,2020 This thesis presents a model predictive control MPC algorithm for solving the cooperative hunting problem with multiple unmanned aerial vehicles UAVs in obstacle rich and moving obstacle environments and builds upon the MPC algorithm using a reinforcement learning method called Guided Policy Search GPS The cooperative hunting problem deals with surrounding a target while navigating around obstacles and avoiding collisions and the MPC algorithm combines the cooperative hunting objective with planning and obstacle avoidance Simulation results show that the MPC algorithm successfully surrounds the target in both scenarios Local minima are avoided for obstacle rich environments and the obstacle interaction is minimized in moving obstacle environments

Furthermore the MPC algorithm was validated with physical quadrotors Finally the GPS algorithm improves upon the MPC solutions by reducing the trajectory length and capture time and then uses the improved trajectories to train a global neural network policy

Uav-based Remote Sensing Felipe Gonzalez Toro (Ed.),2018-04-27 Active technological development has fuelled rapid growth in the number of Unmanned Aerial Vehicle UAV platforms being deployed around the globe Novel UAV platforms UAV based sensors robotic sensing and imaging techniques the development of processing workflows as well as the capacity of ultra high temporal and spatial resolution data provide both opportunities and challenges that will allow engineers and scientists to address novel and important scientific questions in UAV and sensor design remote sensing and environmental monitoring This work features papers on UAV sensor design improvements in UAV sensor technology obstacle detection methods for measuring optical flow target tracking gimbal influence on the stability of UAV images augmented reality tools segmentation in digital surface models for 3D reconstruction detection location and grasping objects multi target localization vision based tracking in cooperative multi UAV systems noise suppression techniques rectification for oblique images two UAV communication system fuzzy based hybrid control algorithms pedestrian detection and tracking as well as a range of atmospheric geological agricultural ecological reef wildlife building and construction coastal area coverage search and rescue SAR water plume temperature measurements aeromagnetic and archaeological surveys applications

**Autonomous and Cooperative Multi-UAV Guidance in Adversarial Environment** Ugur Zengin,2007 The research presented in this dissertation is aimed at developing rule based autonomous and cooperative guidance strategies for UAVs to perform missions such as path planning target tracking and rendezvous while reducing their risk threat exposure level and avoiding threats and or obstacles by utilizing measurement information provided by sensors

*UAVs and Urban Spatial Analysis* Tony H. Grubestic,Jake R. Nelson,2021-01-11 This book provides an introduction to the use of unmanned aerial vehicles UAVs for the geographic observation and spatial analysis of urban areas The velocity of urban change necessitates observation platforms that not only enhance situational awareness for planning and allied analytical efforts but also provide

the ability to rapidly and inexpensively collect data and monitor change UAVs can accomplish both of these tasks but their use in urban environments is loaded with social operational regulatory and technical challenges that must be addressed for successful deployments The book provides a resource for educators and students who work with geographic information and are seeking to enhance these data with the use of unmanned aerial vehicles Topics covered include 1 a primer on UAVs and the many different ways they can be used for geographic observation 2 a detailed overview on the use of aviation maps and charts for operating UAVs in complex urban airspace 3 techniques for integrating UAV derived data with more traditional geographic information 4 application of spatial analytical tools for urban and environmental planning and 5 an exploration of privacy and public safety issues associated with UAV operation

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