Marine Control Systems Guidance Navigation And Control Of Ships Rigs And Underwater Vehicles

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Selected Papers of the Itzhack Y. Bar-Itzhack Memorial Symposium on Estimation, Navigation, and Spacecraft Control CRC Press
A classic in underwater robotics. One of the first volumes in the “Springer Tracts in Advanced Robotics” series, it has been a bestseller through the previous three editions. Fifteen years after the publication of the first edition, the fourth edition comes to print. The book addresses the main control aspects in underwater manipulation tasks. With respect to the third edition, it has been revised, extended and some concepts better clustered. The mathematical model with significant impact on the control strategy is discussed. The problem of controlling a 6-degrees-of-freedoms autonomous underwater vehicle is 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.
Intelligent Marine Robotics Modelling, Simulation and Applications John Wiley & Sons
This book presents a series of innovative technologies and research results on adaptive control of dynamic systems with quantization, uncertainty, and nonlinearity, including the theoretical success and practical development such as the approaches for stability analysis, the compensation of quantization, the treatment of subsystem interactions, and the improvement of system tracking and transient performance. Novel solutions by adopting backstepping design tools to a number of

hotspots and challenging problems in the area of adaptive control are provided. In the first three chapters, the general design procedures and stability analysis of backstepping controllers and the basic descriptions and properties of quantizers are introduced as preliminary knowledge for this book. In the remainder of this book, adaptive control schemes are introduced to compensate for the effects of input quantization, state quantization, both input and state/output quantization for uncertain nonlinear systems and are applied to helicopter systems and DC Microgrid. Discussion remarks are provided in each chapter highlighting new approaches and contributions to emphasize the novelty of the presented design and analysis methods. Simulation results are also given in each chapter to show the effectiveness of these methods. This book is helpful to learn and understand the fundamental backstepping schemes for state feedback control and output feedback control. It can be used as a reference book or a textbook on adaptive quantized control for students with some background in feedback control systems. Researchers, graduate students, and engineers in the fields of control, information, and communication, electrical engineering, mechanical engineering, computer science, and others will benefit from this book.

Advanced Control Methods in Marine Robotics Applications BoD – Books on Demand

At publication, The Control Handbook immediately became the definitive resource that engineers working with modern control systems required. Among its many accolades, that first edition was cited by the AAP as the Best Engineering Handbook of 1996. Now, 15 years later, William Levine has once again compiled the most comprehensive and authoritative resource on control engineering. He has fully reorganized the text to reflect the technical advances achieved since the last edition and has expanded its contents to include the multidisciplinary perspective that is making control engineering a critical component in so many fields. Now expanded from one to three volumes, The Control Handbook, Second Edition brilliantly organizes cutting-edge contributions from more than 200 leading experts representing every corner of the globe. They cover everything from basic closed-loop systems to multi-agent adaptive systems and from the control of electric motors to the control of complex networks. Progressively organized, the three volume set includes: Control System Fundamentals Control System Applications Control System Advanced Methods Any practicing engineer, student, or researcher working in fields as diverse as electronics, aeronautics, or biomedicine will find this handbook to be a time-saving resource filled with invaluable formulas, models, methods, and innovative thinking. In fact, any physicist, biologist, mathematician, or researcher in any number of fields developing or improving products and systems will find the answers and ideas they need. As with the first edition, the new edition not only stands as a record of accomplishment in control engineering but provides

researchers with the means to make further advances.

Maritime Engineering and Technology Springer

Cooperative Control Design: A Systematic, Passivity-Based Approach discusses multi-agent coordination problems, including formation control, attitude coordination, and synchronization. The goal of the book is to introduce passivity as a design tool for multi-agent systems, to provide exemplary work using this tool, and to illustrate its advantages in designing robust cooperative control algorithms. The discussion begins with an introduction to passivity and demonstrates how passivity can be used as a design tool for motion coordination. Followed by the case of adaptive redesigns for reference velocity recovery while describing a basic design, a modified design and the parameter convergence problem. Formation control is presented as it relates to relative distance control and relative position control. The coverage is concluded with a comprehensive discussion of agreement and the synchronization problem with an example using attitude coordination.

Constrained Control and Estimation Institution of Engineering and Technology

This book presents selected papers of the Itzhack Y. Bar-Itzhack Memorial Sympo- sium on Estimation, Navigation, and Spacecraft Control. Itzhack Y. Bar-Itzhack, professor Emeritus of Aerospace Engineering at the Technion – Israel Institute of Technology, was a prominent and world-renowned member of the applied estimation, navigation, and spacecraft attitude determination communities. He touched the lives of many. He had a love for life, an incredible sense of humor, and wisdom that he shared freely with everyone he met. To honor Professor Bar-Itzhack's memory, as well as his numerous seminal professional achievements, an international symposium was held in Haifa, Israel, on October 14 – 17, 2012, under the auspices of the Faculty of Aerospace Engineering at the Technion and the Israeli Association for Automatic Control. The book contains 27 selected, revised, and edited contributed chapters written by eminent international experts. The book is organized in three parts: (1) Estimation, (2) Navigation and (3) Spacecraft Guidance, Navigation and Control. The volume was prepared as a reference for research scientists and practicing engineers from academy and industry in the fields of estimation, navigation, and spacecraft GN&C.

The Control Handbook (three volume set) Springer Science & Business Media

The main objective of this monograph is to present a broad range of well worked out, recent application studies as well as theoretical contributions in the field of sliding mode control system analysis and design. The contributions presented here include new theoretical developments as well as successful applications of variable structure controllers primarily in the field of power electronics, electric drives and motion steering systems. They enrich the current state of the art, and motivate and encourage new ideas and solutions in the sliding mode control area.

Underwater Robots Springer Science & Business Media

Time-Critical Cooperative Control of Autonomous Air Vehicles presents, in an easy-to-read style, the latest research conducted in the industry, while also introducing a set of novel ideas that illuminate a new approach to problem-solving. The book is virtually self-contained, giving the reader a complete, integrated presentation of the different concepts, mathematical tools, and control solutions needed to tackle and solve a number of problems concerning time-critical cooperative control of UAVs. By including case studies of fixed-wing and multirotor UAVs, the book effectively broadens the scope of application of the methodologies developed. This theoretical presentation is complemented with the results of flight tests with real UAVs, and is an ideal reference for researchers and practitioners from academia, research labs, commercial companies, government workers, and those in the international aerospace industry. Addresses important topics related to time-critical cooperative control of UAVs Describes solutions to the problems rooted in solid dynamical systems theory Applies the solutions developed to fixed-wing and multirotor UAVs Includes the results of field tests with both classes of UAVs

Proceedings of the 12th International Conference on Marine Navigation and Safety of Sea Transportation (TransNav 2017), June 21-23, 2017, Gdynia, Poland Springer Science & Business Media

Robotics is undergoing a major transformation in scope and dimension. From a largely dominant industrial focus, robotics is rapidly expanding into human en- ronments and vigorously engaged in its new challenges. Interacting with, assi- ing, serving, and exploring with humans, the emerging robots will increasingly touch people and their lives. Beyond its impact on physical robots, the body of knowledge robotics has p- duced is revealing a much wider range of applications reaching across diverse research areas and scientific disciplines, such as: biomechanics, haptics, neuros- ences, virtual simulation, animation, surgery, and sensor networks among others. In return, the challenges of the new emerging areas are proving an abundant source of stimulation and insights for the field of robotics. It is indeed at the int- section of disciplines that the most striking advances happen. The Springer Tracts in Advanced Robotics (STAR) is devoted to bringing to the research community the latest advances in the robotics field on the basis of their significance and quality. Through a wide and timely dissemination of critical - search developments in robotics, our objective with this series is to promote more exchanges and collaborations among the researchers in the community and c- tribute to further advancements in this rapidly growing field.

Proceedings of the 3rd International Conference on Maritime Technology and Engineering (MARTECH 2016, Lisbon, Portugal, 4-6 July 2016) CRC Press

Following the successful 1st CEAS (Council of European Aerospace Societies) Specialist Conference on Guidance, Navigation and Control (CEAS EuroGNC) held in Munich, Germany in 2011, Delft University of Technology happily accepted the invitation of organizing the 2nd CEAS EuroGNC in Delft, The Netherlands in 2013. The goal of the conference is to promote new advances in aerospace GNC theory and technologies for enhancing safety, survivability, efficiency, performance, autonomy and intelligence of aerospace systems using on-board sensing, computing and systems. A great push for new developments in GNC are the ever higher safety and sustainability requirements in aviation. Impressive progress was made in new research fields such as sensor and actuator fault detection and diagnosis, reconfigurable and fault tolerant flight control, online safe flight envelop prediction and protection, online global aerodynamic model identification, online global optimization and flight upset recovery. All of these challenges depend on new online solutions from on-board computing systems. Scientists and engineers in GNC have been developing model based, sensor based as well as knowledge based approaches aiming for highly robust, adaptive, nonlinear, intelligent and autonomous GNC systems. Although the papers presented at the conference and

selected in this book could not possibly cover all of the present challenges in the GNC field, many of them have indeed been addressed and a wealth of new ideas, solutions and results were proposed and presented. For the 2nd CEAS Specialist Conference on Guidance, Navigation and Control the International Program Committee conducted a formal review process. Each paper was reviewed in compliance with good journal practice by at least two independent and anonymous reviewers. The papers published in this book were selected from the conference proceedings based on the results and recommendations from the reviewers.

Sliding Mode Control Springer

This book highlights the latest achievements concerning the theory, methods and practice of fault diagnostics, fault tolerant systems and cyber safety. When considering the diagnostics of industrial processes and systems, increasingly important safety issues cannot be ignored. In this context, diagnostics plays a crucial role as a primary measure of the improvement of the overall system safety integrity level. Obtaining the desired diagnostic coverage or providing an appropriate level of inviolability of the integrity of a system is now practically inconceivable without the use of fault detection and isolation methods. Given the breadth and depth of its coverage, the book will be of interest to researchers faced with the challenge of designing technical and medical diagnosis systems, as well as junior researchers and students in the fields of automatic control, robotics, computer science and artificial intelligence.

Stabilization, Tracking and Formation Control of Autonomous Marine Vessels Springer

This thesis proposes a novel Model Predictive Control (MPC) strategy, which modifies the usual MPC cost function in order to achieve a desirable sparse actuation. It features an l1-regularised least squares loss function, in which the control error variance competes with the sum of input channels magnitude (or slew rate) over the whole horizon length. While standard control techniques lead to continuous movements of all actuators, this approach enables a selected subset of actuators to be used, the others being brought into play in exceptional circumstances. The same approach can also be used to obtain asynchronous actuator interventions, so that control actions are only taken in response to large disturbances. This thesis presents a straightforward and systematic approach to achieving these practical properties, which are ignored by mainstream control theory.

Springer

Most ocean vessels are underactuated but control of their motion in the real ocean environment is essential. Starting with a review of the background on ocean-vessel dynamics and nonlinear control theory, the authors ' systematic approach is based on various nontrivial coordinate transformations coupled with advanced nonlinear control design methods. This strategy is then used for the development and analysis of a number of ocean-vessel control systems with the aim of achieving advanced motion control tasks including stabilization, trajectory-tracking, path-tracking and path-following. Control of Ships and Underwater Vehicles offers the reader: - new results in the nonlinear control of underactuated ocean vessels; - efficient designs for the implementation of controllers on underactuated ocean vessels; - numerical simulations and real-time implementations of the control systems designed on a scale-model ship for each controller developed to illustrate their effectiveness and afford practical guidance.

Navigation and Control of Autonomous Marine Vehicles Springer Science & Business Media

Recent developments in constrained control and estimation have created a need for this comprehensive introduction to the underlying fundamental principles. These advances have significantly broadened the realm of application of constrained control. - Using the principal tools of prediction and optimisation, examples of how to deal with constraints are given, placing emphasis on model predictive control. - New results combine a number of methods in a

unique way, enabling you to build on your background in estimation theory, linear control, stability theory and state-space methods. - Companion web site, continually updated by the authors. Easy to read and at the same time containing a high level of technical detail, this self-contained, new approach to methods for constrained control in design will give you a full understanding of the subject.

Autonomous Underwater Vehicles Springer
A comprehensive and extensive study of the latest research in control systems for marine vehicles. Demonstrates how the implementation of mathematical models and modern control theory can reduce fuel consumption and improve reliability and performance. Coverage includes ocean vehicle modeling, environmental disturbances, the dynamics and stability of ships, sensor and navigation systems. Numerous examples and exercises facilitate understanding.

Design for Underactuated and Nonlinear Marine Systems BoD – Books on Demand
This edited volume includes thoroughly collected on sensing and control for autonomous vehicles. Guidance, navigation and motion control systems for autonomous vehicles are increasingly important in land-based, marine and aerial operations. Autonomous underwater vehicles may be used for pipeline inspection, light intervention work, underwater survey and collection of oceanographic/biological data. Autonomous unmanned aerial systems can be used in a large number of applications such as inspection, monitoring, data collection, surveillance, etc. At present, vehicles operate with limited autonomy and a minimum of intelligence. There is a growing interest for cooperative and coordinated multi-vehicle systems, real-time re-planning, robust autonomous navigation systems and robust autonomous control of vehicles. Unmanned vehicles with high levels of autonomy may be used for safe and efficient collection of environmental data, for assimilation of climate and environmental models and to complement global satellite systems. The target audience primarily comprises research experts in the field of control theory, but the book may also be beneficial for graduate students.

Advanced Solutions in Diagnostics and Fault Tolerant Control John Wiley & Sons
This book is intended to meet the needs of those who seek to develop control systems for ROVs when there is no model available during the initial design stage. The modeling, simulation and application of marine vehicles like underwater robotic vehicles (URVs) are multidisciplinary, and combine mathematical aspects from various engineering disciplines. URVs such as remotely operated vehicle (ROVs) are used for a wide range of applications such as exploring the extreme depths of our ocean, where a hard-wired link is still required. Most ROVs operate in extreme environments with uncertainties in the model prior to control system design. However, the method involved extensive testing before the system model could be used for any control actions. It has been found that the range of error can be extensive and uncertain in actual, continuously varying conditions. Hence, it is important to address the problem of reliance on model testing using different modeling approaches. In this book, approaches such as WAMIT, ANSYS-CFX, STAR CCM+, MATLAB and Simulink are used to model parameters for ROVs. A few benchmark models are provided, allowing researchers and students to explore and test different control schemes. Given its scope, the book offers a valuable reference guide for postgraduate and undergraduate students engaged in modeling and simulation for ROV control.

4th International Conference, MESAS 2017, Rome, Italy, October 24-26, 2017, Revised Selected Papers Springer Nature
Robotic marine vessels can be used for a wide range of purposes, including defence, marine

science, offshore energy and hydrographic surveys, and environmental surveys and protection. Such vessels need to meet a variety of criteria: they must be able to operate in salt water, and to communicate and be controlled over large distances, even when submerged or in inclement weather. Further challenges include 3D navigation of individual vehicles, groups or squadrons. This book covers the current state of research in navigation, modelling and control of marine autonomous vehicles, and deals with various related topics, including collision avoidance, communication, and a range of applications. It provides valuable insights for an audience of researchers, academics and postgraduate students interested in autonomous marine vessels, robotics, and electrical and automobile engineering.

Control Applications in Marine Systems 1998 Marine Control SystemsGuidance, Navigation and Control of Ships, Rigs and Underwater VehiclesHandbook of Marine Craft Hydrodynamics and Motion Control This textbook offers a comprehensive introduction to the control of marine vehicles, from fundamental to advanced concepts, including robust control techniques for handling model uncertainty, environmental disturbances, and actuator limitations. Starting with an introductory chapter that extensively reviews automatic control and dynamic modeling techniques for ocean vehicles, the first part of the book presents in-depth information on the analysis and control of linear time invariant systems. The concepts discussed are developed progressively, providing a basis for understanding more complex techniques and stimulating readers' intuition. In addition, selected examples illustrating the main concepts, the corresponding MATLAB ® code, and problems are included in each chapter. In turn, the second part of the book offers comprehensive coverage on the stability and control of nonlinear systems. Following the same intuitive approach, it guides readers from the fundamentals to more advanced techniques, which culminate in integrator backstepping, adaptive and sliding mode control. Leveraging the author's considerable teaching and research experience, the book offers a good balance of theory and stimulating questions. Not only does it provide a valuable resource for undergraduate and graduate students; it will also benefit practitioners who want to review the foundational concepts underpinning some of the latest advanced marine vehicle control techniques, for use in their own applications.

Benchmark Models of Control System Design for Remotely Operated Vehicles John Wiley & Sons 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

Applications to Land, Water and Air Vehicles

Springer Nature

Dynamics and Control of Mechanical Systems in Offshore Engineering is a comprehensive treatment of marine mechanical systems (MMS) involved in processes of great importance such as oil drilling and mineral recovery. Ranging from nonlinear dynamic modeling and stability analysis of flexible riser systems, through advanced control design for an installation system with a single rigid payload attached by thrusters, to robust adaptive control for mooring systems, it is an authoritative reference on the dynamics and control of MMS. Readers will gain not only a complete picture of MMS at the system level, but also a better understanding of the technical considerations involved and solutions to problems that commonly arise from dealing with them. The text provides: · a complete framework of dynamical analysis and control design for marine mechanical systems; · new results on the dynamical analysis of riser, mooring and installation systems together with a general modeling method for a class of MMS; · a general method and strategy for realizing the control objectives of marine systems with guaranteed stability the effectiveness of which is illustrated by extensive numerical simulation; and · approximation-based control schemes using neural networks for installation of subsea structures with attached thrusters in the presence of time-varying environmental disturbances and parametric uncertainties. Most of the results presented are analytical with repeatable design algorithms with proven closed-loop stability and performance analysis of the proposed controllers is rigorous and detailed. Dynamics and Control of Mechanical Systems in Offshore Engineering is primarily intended for researchers and engineers in the system and control community, but graduate students studying control and marine engineering will also find it a useful resource as will practitioners working on the design, running or maintenance of offshore platforms.