

ROBUST REGION REACHING AND TRACKING
CONTROL OF AN AUTONOMOUS UNDERWATER
VEHICLE

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ROBUST REGION REACHING AND TRACKING
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VEHICLE

by

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in fulfillment of the requirements of the degree of doctor of philosophy

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To my parents

Certificate

This is to certify that the thesis titled “**Robust Region Reaching and Tracking Control of an Autonomous Underwater Vehicle**” submitted by **Koena Mukherjee** to the **Indian Institute of Technology Delhi**, for the award of the degree of **Doctor of Philosophy** in Electrical Engineering, is a record of the original, bonafide research work carried out by her under our supervision. The thesis has reached the standards fulfilling the requirements of the regulations related to the award of the degree.

The results contained in this thesis have not been submitted either in part or in full to any other university or institute for the award of any degree or diploma.

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Abstract

The vast expanse of ocean on earth has permeated interest in researchers to develop autonomous underwater vehicle (AUV) as a tool to study and utilize marine life more appropriately. An underwater vehicle provides a way for interaction and possible manipulation in hazardous and uncertain ocean environment. The focus of this dissertation is to design robust controllers for an AUV, which can navigate in presence of obstacles, input time delay, parametric uncertainty, environmental disturbances, etc.

Presently, most research work focuses on set point regulation and tracking of an AUV based on different mission scenario. This research work utilizes potential field based method to develop a new region reaching/tracking based controller with application to an AUV. Assuming position measurement is available to the controller, an auxiliary velocity signal is generated to eliminate the requirement of velocity measurement. Further, the region reaching based controller design is modified appropriately to avoid static obstacles.

A region tracking controller is developed for an AUV with application to pipeline inspection like scenario. In addition, uncertain restoring forces are estimated using adaptive law and compensated in the closed loop dynamics. To facilitate the design of this controller and analysis, a high pass filter is introduced which obviates the use of velocity sensor.

Leveraging the result obtained during region tracking controller design, a robust controller is designed for an AUV with constant input delay. A rigorous stability analysis using Lyapunov-Krasovskii functional is performed to prove Uniformly Ultimately Bounded (UUB) stability of the closed loop system.

Since environmental disturbances such as waves, currents generally affect an AUV

operation, a nonlinear disturbance observer (DO) structure is proposed to estimate the disturbance. An exo-system is used to generate the disturbance with unknown amplitude and phase. The observer estimates the state of the exo-system and the disturbance is canceled out in the composite closed loop dynamics. Extending the previous results obtained for DO, a new DO is presented to estimate periodic disturbances with unknown amplitude, phase and frequency. The unknown frequency is estimated using adaptive control technique and bounds of the unknown quantities are used to achieve asymptotic stability of the composite closed loop dynamics.

Lyapunov based stability analyses and simulations are provided to demonstrate the performance of each of the controller and observer designed throughout the dissertation.

Contents

Certificate	i
Acknowledgements	iii
Abstract	v
List of Figures	xi
List of Tables	xiii
Abbreviation/Nomenclature	xv
1 Introduction	1
1.1 Motivation and Literature Survey	2
1.2 Issues in AUV Control	5
1.2.1 Region Reaching Controller	5
1.2.2 Region Tracking Controller	9
1.2.3 Compensation of Input delay	11
1.2.4 Compensation of External Disturbances	12
1.3 Problem Formulation	14
1.4 Organization of the Thesis	18
2 AUV Modeling	21
2.1 Introduction	21
2.2 Kinematics	22
2.2.1 Reference Frames	22

2.2.2	Euler Angle Representation	24
2.2.3	Quaternion Representation	26
2.3	Dynamics	27
2.4	Hydrodynamic Parameters	30
2.4.1	Added Mass	30
2.4.2	Damping	31
2.5	Hydrostatic Forces	33
2.6	Nonlinear Equation of Motion & Properties	35
2.7	Environmental Disturbance	37
2.8	Submodels	38
2.8.1	Speed Control Model	39
2.8.2	Vertical Plane Model	39
2.8.3	Horizontal Plane Model	40
2.9	Summary	40
3	Region Reaching Control without Velocity Measurement	41
3.1	Introduction	41
3.2	Concept of Region Reaching	43
3.3	Region Reaching Control without Velocity Measurement	47
3.3.1	Controller Design	48
3.3.2	Stability Analysis	50
3.4	Obstacle avoidance without Velocity Measurement	52
3.4.1	Controller Design	52
3.4.2	Stability Analysis	53
3.5	Simulation Results	55
3.5.1	Region Reaching Control	55
3.5.2	Obstacle Avoidance	57
3.6	Summary	59
4	Region Tracking Control without Velocity Measurement	61
4.1	Introduction	61

4.2	Concept of Region Tracking	62
4.3	Region Tracking Control without Velocity Measurement	65
4.3.1	Controller Design	67
4.3.2	Stability Analysis	68
4.4	Robust Adaptive Region Tracking Controller for an AUV	72
4.4.1	Filtered Tracking Error & Control Development	73
4.4.2	Stability Analysis	76
4.5	Simulation Studies	80
4.5.1	Region tracking control without gravitational force compensation	80
4.5.2	Region tracking control with gravitational force compensation .	81
4.6	Summary	83
5	Input Delay Compensation	85
5.1	Introduction	85
5.2	Region Tracking Control of AUV with Input Delay Compensation . . .	86
5.2.1	Controller Design	87
5.2.2	Stability Analysis	90
5.3	Simulation Results	96
5.4	Summary	98
6	Disturbance Observer Design for External Disturbances	101
6.1	Introduction	101
6.2	External Disturbances with Unknown Amplitude and Phase	103
6.2.1	Controller Design	104
6.2.2	Exo-system and the Disturbance Observer	105
6.2.3	Composite Disturbance Observer Model	109
6.3	Periodic Disturbances with Unknown Amplitude, Phase and Frequency	113
6.3.1	Controller design	113
6.3.2	Disturbance Observer Design	114
6.3.3	Stability Analysis	119
6.3.4	Algorithmic Steps	124

6.4	Simulation Study	125
6.4.1	Disturbance Observer for known frequency	125
6.4.2	Disturbance Observer for unknown frequency	126
6.5	Summary	128
7	Conclusion	131
7.1	Summary	131
7.2	Future Scope of Work	133
	References	135
	Appendices	147
A	ODIN AUV MODEL PARAMETERS	149
B	BOUND FOR STATE-DEPENDENT TERM	153
C	TIME DERIVATIVE OF L-K FUNCTIONAL	155
	Biodata	159

List of Figures

1.1	Objective function for a specified region	6
1.2	Vehicle monitoring a ridge like area	8
1.3	Illustration of region reaching and tracking control respectively	9
2.1	ECEF frame $X_e Y_e Z_e$ is rotating with angular velocity ω with respect to ECIF frame $X_i Y_i Z_i$. Figure shows NED frame pointing towards actual North-East-Down direction and Body frame $X_B Y_B Z_B$ attached to the moving vehicle.	23
2.2	Inertial $\{I\}$ and Body coordinate frame $\{B\}$	25
2.3	Rigid Body (RB) with body fixed frame $\{B\}$ rotating with respect to inertial frame $\{I\}$ with ω angular velocity.	28
2.4	Boundary layer development on a streamlined body and a bluff body, subjected to an adverse pressure gradient.	32
2.5	Restoring forces acting on an underwater vehicle	33
3.1	Illustration of region based task performed by an AUV: Oceanographic survey	42
3.2	Illustration of region based task performed by an UVMS: Pipeline inspection and maintenance	43
3.3	Objective function for a specified region	44
3.4	AUV moving towards subregion with radius $(r_1 - r_2)$ and a fixed set-point	45
3.5	Illustration of potential energy function	46
3.6	Illustration of variation in potential energy function with change in position error	47

3.7	Navigation of an underwater vehicle to a specific point within a desired region	56
3.8	Evolution of regulation errors with time	56
3.9	Control force for region reaching and set point regulation in x-direction	57
3.10	Control force for region reaching and set point regulation in z-direction	57
3.11	Position measurement is affected by a Gaussian distributed random noise	58
3.12	Navigation of an underwater vehicle to a specific point within a desired region	59
3.13	Region reaching with static obstacle avoidance	59
4.1	Illustration of region based task of an AUV: Pipeline inspecion	63
4.2	Controller block diagram	67
4.3	Visual illustration of the definition	69
4.4	Controller block diagram	75
4.5	Evolution of actual and desired position with time	81
4.6	Control torque (Nm) for region tracking	82
4.7	Time history of pose error with time (s)	82
4.8	Estimated parameters of unknown gravitational force	83
5.1	Controller block diagram	89
5.2	Plot for region tracking variable in x-direction with different input delays	97
5.3	Plot for region tracking variable in z-direction with different input delays	98
5.4	Evolution of control torque for region tracking using proposed controller	98
6.1	Composite controller-observer structure	110
6.2	Plot for time evolution of position and orientation error variable	125
6.3	Observer error dynamics for $\omega_o = 2Hz$	126
6.4	Plot for time evolution of position and orientation error variable in x, y and z direction.	128
6.5	Plot for time evolution of linear and angular velocity error variable in x, y and z direction.	128
6.6	Estimated disturbance error with time	129

List of Tables

2.1	SNAME Notations	23
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Abbreviations and Nomenclature

Abbreviation/Symbol	Description
AUV	Autonomous Underwater Vehicle
ROV	Remotely Operated Vehicle
DOF	Degrees of Freedom
UUB	Uniformly Ultimately Bounded
UVMS	Underwater Vehicle Manipulator Systems
DO	Disturbance Observer
LIP	Linear-In-Parameter
APF	Artificial Potential Field
$\eta_1 = [x, y, z]^T$	Cartesian position coordinate
$\eta_2 = [\phi, \theta, \psi]^T$	Orientation in Euler angle notation
$\epsilon = [\epsilon_0, \epsilon_1, \epsilon_2, \epsilon_3]^T$	Quaternion
$\eta = [\eta_1^T, \eta_2^T]^T$	Pose Vector
η^T	Transpose of a vector
R	Rotation matrix
x_d, y_d, z_d	Desired Cartesian position coordinate
ϕ_d, θ_d, ψ_d	Desired orientation in Euler angle notation
$e_x = x - x_d$	x-position error
$e_1 = [e_x, e_y, e_z]^T$	Positional error
$e_2 = [e_\phi, e_\theta, e_\psi]^T$	Orientation error
$e = [e_1^T, e_2^T]^T$	Pose error
e_R	Region tracking error
Ra	Attractive region
Rr	Repulsive region
τ_c	Controller input
τ_d	Delay in input
d	Disturbance
M	Mass matrix
C	Coriolis and Centrifugal matrix
D	Damping matrix
$g(\eta)$	Gravitational force matrix
V	Lyapunov function
I_n	Identity Matrix of dimension $n \times n$
$\mathcal{L}_\infty$	∞ -norm
$\mathcal{L}_2$	2-norm
$Tanh(X)$	$[\tanh(x_1), \dots, \tanh(x_n)]^T$
$Cosh(X)$	$[\cosh(x_1), \dots, \cosh(x_n)]^T$
$L_N Cosh(X)$	$[\ln \cosh(x_1), \dots, \ln \cosh(x_n)]^T$
$\lambda_{min}\{P\}/\lambda_{max}\{P\}$	Minimum/Maximum Eigenvalue of matrix P