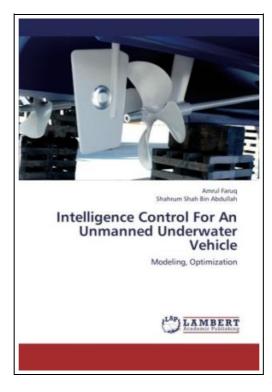
Intelligence Control For An Unmanned Underwater Vehicle



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INTELLIGENCE CONTROL FOR AN UNMANNED UNDERWATER VEHICLE



Condition: New. Publisher/Verlag: LAP Lambert Academic Publishing | Modeling, Optimization | Underwater environment poses a difficult challenge for autonomous underwater navigation. A standard problem of underwater vehicles is to maintain it position at a certain depth in order to perform desired operations. An effective controller is required for this purpose and hence the design of a depth controller for an Unmanned Underwater Vehicle is described in this book. The control algorithm is simulated by using the Marine Guidance Navigation and Control Simulator. The project shows a Radial Basis Function Metamodel can be used to tune the scaling factors of a Fuzzy Logic Controller. By using offline optimization approach, a comparison between Genetic Algorithm and Metamodeling has been done to minimize the Integral Square Error between the set point and the measured depth of the underwater vehicle. The results showed that it is possible to obtain a reasonably good error using Metamodeling approach in much a shorter time compared to the Genetic Algorithm approach. | Format: Paperback | Language/Sprache: english | 113 gr | 220x150x4 mm | 72 pp.

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