## Great Lakes Conference 2018

# Autonomous Vehicles for Exploration, Mapping and Environmental Monitoring

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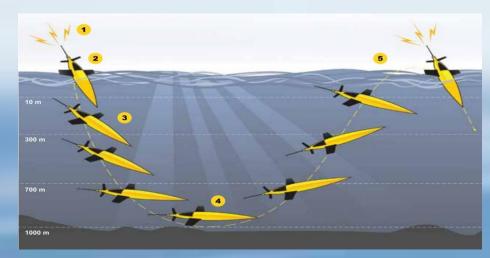
Summary of **Autonomous Marine Vehicles** used in **Great Lakes Research** and **Time Spent on the Surface** 



# Autonomous Underwater Vehicles (AUVs)

• Sea Gliders:

On the surface very little



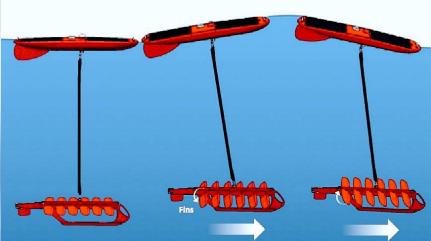
Autonomous Underwater Vehicles (AUVs)
 Start and end on the surface



# Autonomous Surface Vehicles (ASVs)

Wave Gliders

Have a surface presence 100%



Autonomous Surface Vessels (ASVs)







#### Never leave the surface



# **Examples of Great Lakes Efforts**

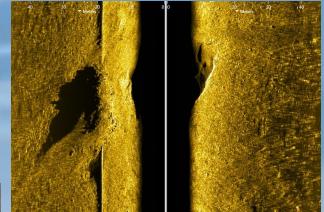
- USGS Wave Glider Winter 2012
- LLO & UM
   Sea Glider





- Mich Tech Iver3/EdgeTech 2205
- CIGLR Water Quality
- Others







# Autonomous Surface Vehicle Workshop

- Solomons, MD (November, 2015)
   Alliance for Coastal Technologies
- Funded by NOAA/IOOS



- Shallow Water Mapping and Water Quality Monitoring
- Aid in Transition of Evolving Technologies from Research Tools to Operational Tools
- Opportunities in the User Market, Performance Parameters, and Cost Considerations

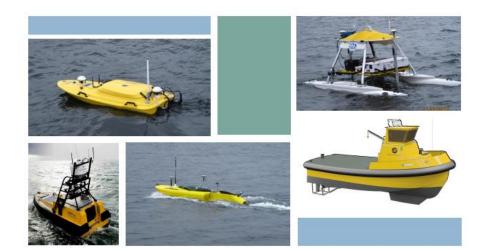


# Workshop Report



# Autonomous Surface Vehicle Workshop

#### PROCEEDINGS



November 18-20, 2015 Solomons, MD

http://www.act-us.info/workshops.php



### **Advanced Underwater Mapping**



**Full Autonomous Underwater Vehicle** 



**Remotely Operated Vehicles** 

Submerged Petroleum Pipeline

> Autonomous Underwater Vehicle (AUV) Survey

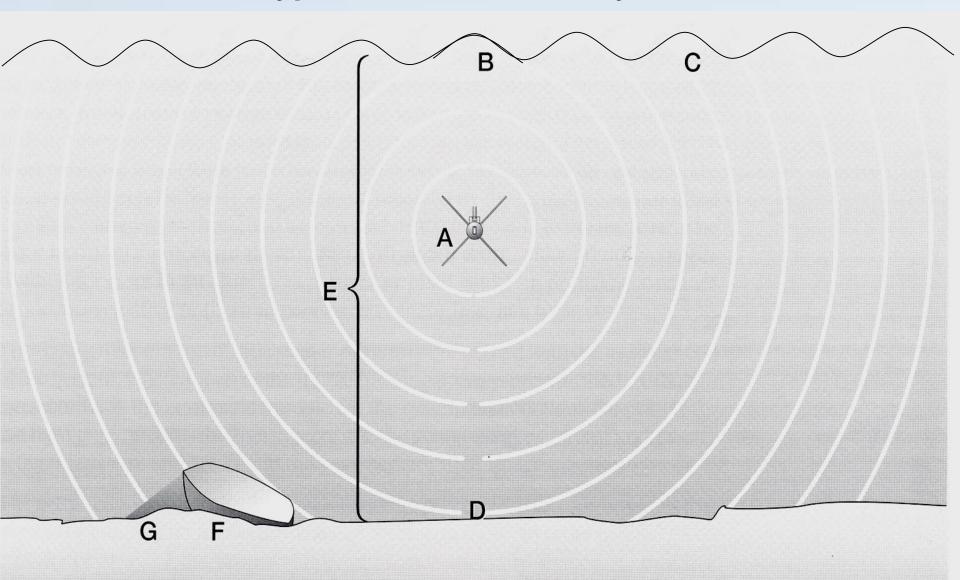
Ultra High Resolution Side Scan Sonar Image Swath Width = 160 m

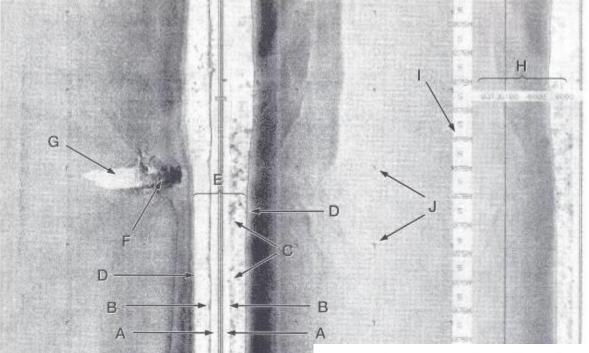
## Autonomous Underwater Vehicle (AUV)



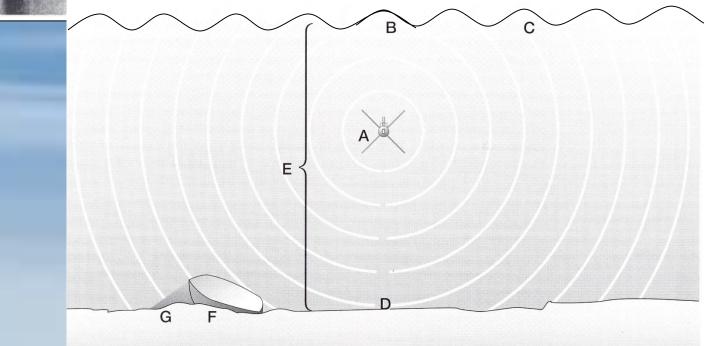
#### Side Scan Sonar

#### **Typical Sound Geometry**





- A: Trigger pulse
- **B:** First surface return
- C: Sea clutter
- **D:** First bottom return
- E: Water column
- F: Sunken fishing vessel
- **G:** Shadow



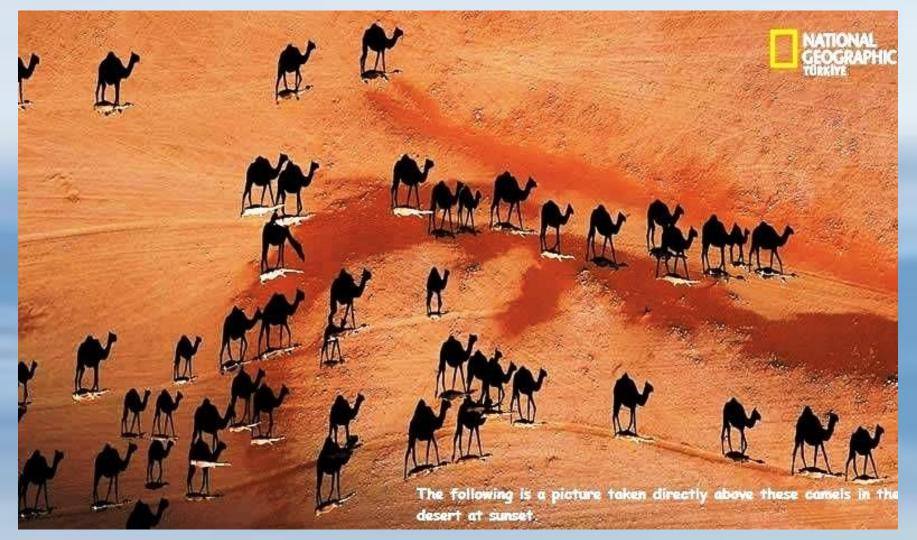
# Side Scan Sonar An "Active Remote Sensor"

Theory of Operation



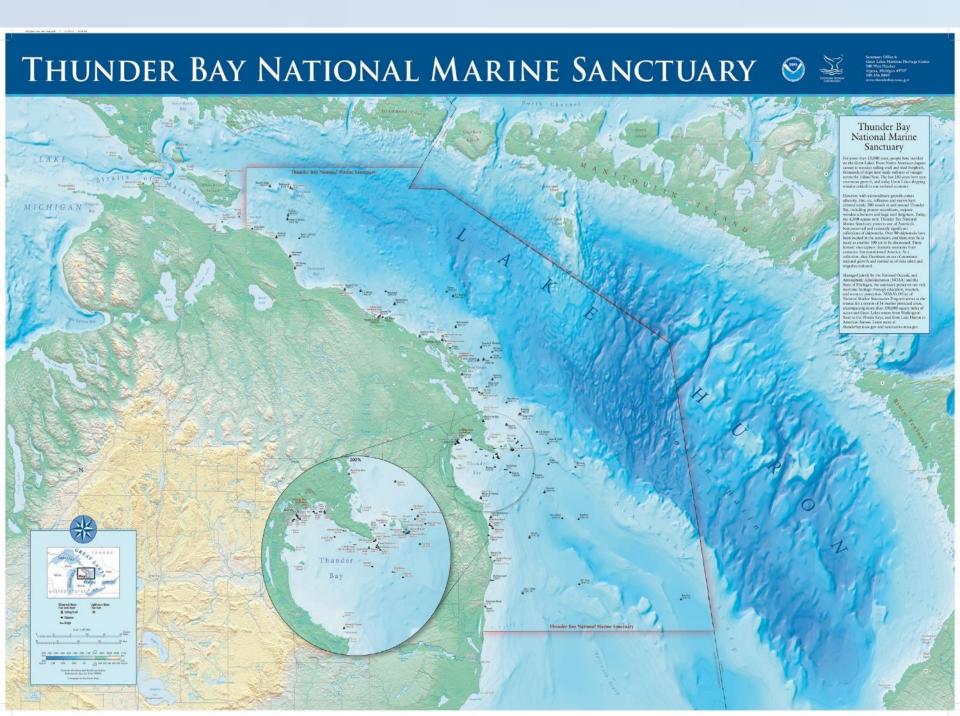


## Result





# An image made from sound, as the illuminating source











Phase I: Over-Water UAS Survey (April)
Phase II: Exploratory Sonar Survey (May)
Phase III: Targeted Acoustic Survey via AUV (June)
Phase IV: Diving Operations for Photogrammetric Modeling (July)

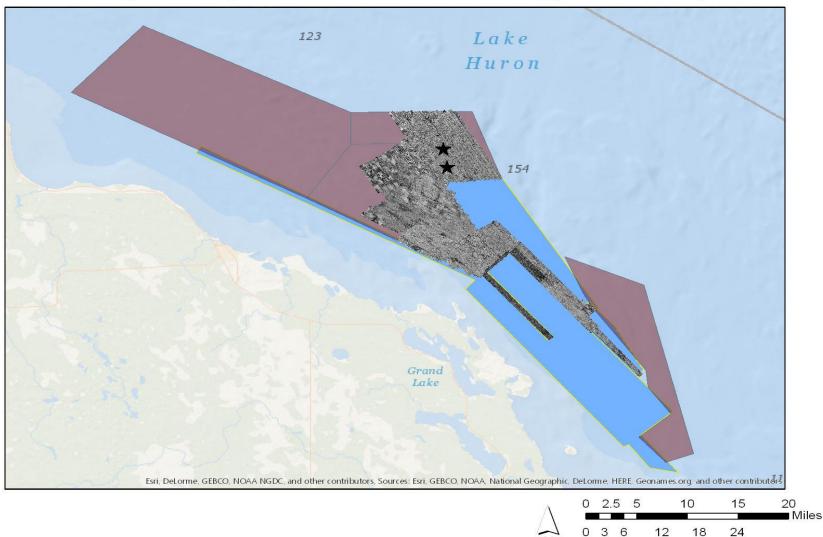
**Follow-Up Investigation:** ROV Mission to Newly Discovered Sites (August)



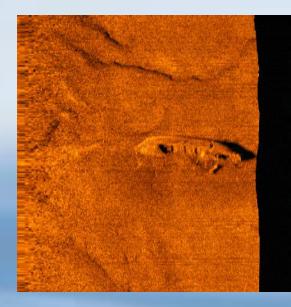


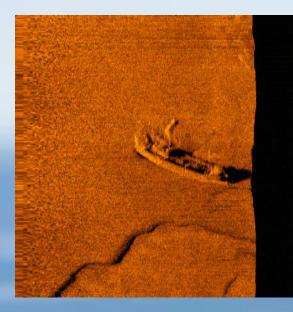
Kilometers

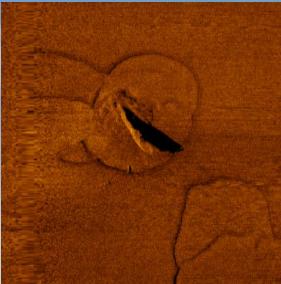
#### Area Covered During 2017 Field Operations Nintey-Four Square Miles of Lake Floor Mapped in Six Days

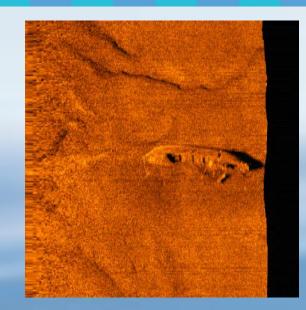












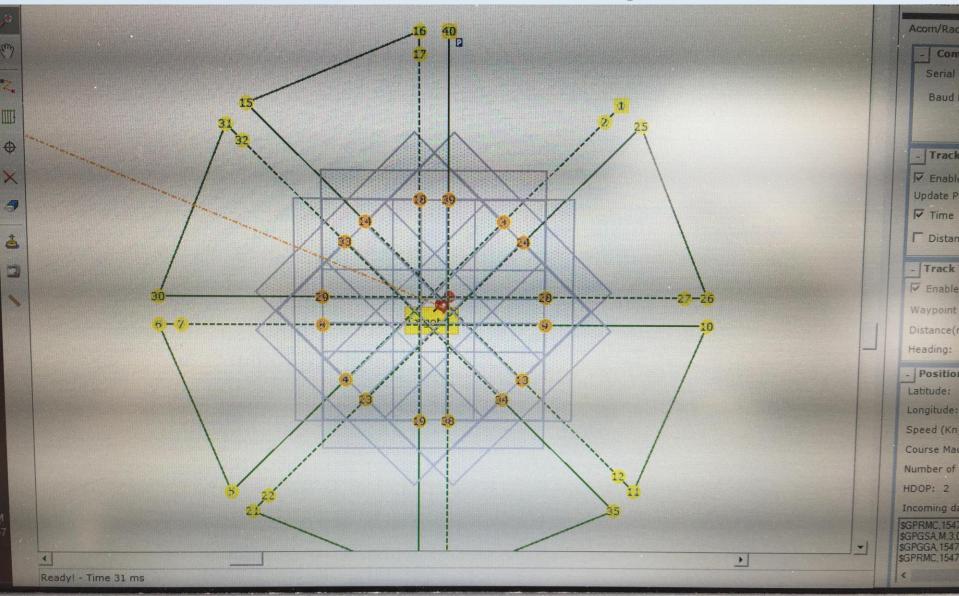


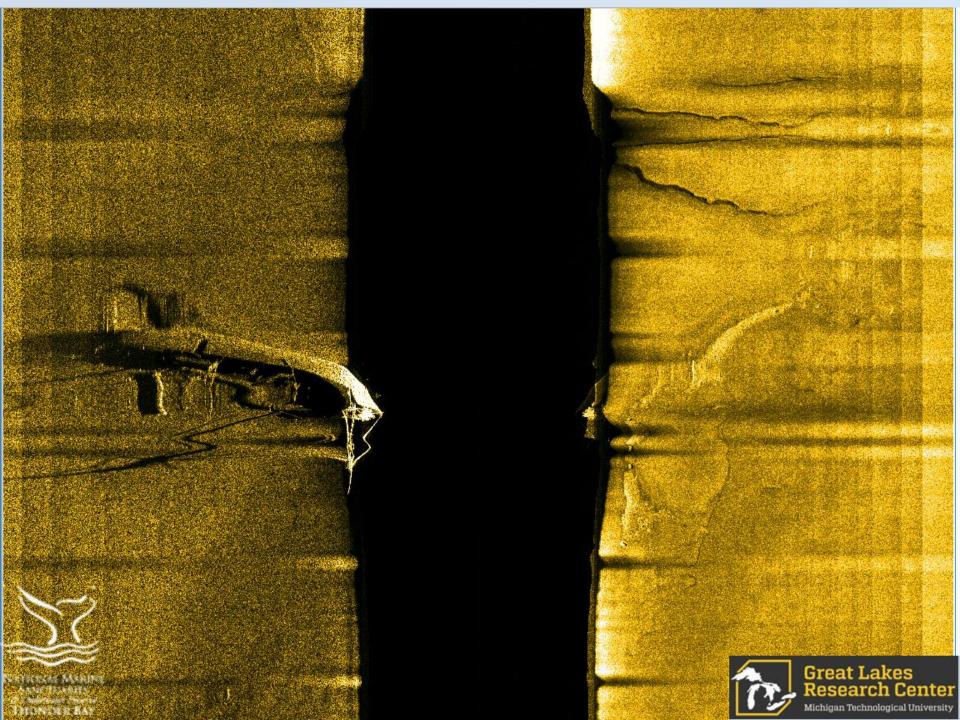


#### Phase III: Target Survey with AUV



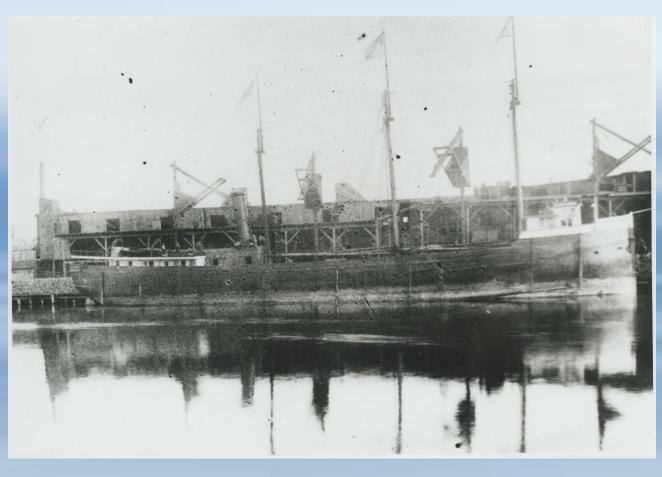
### Target Identification Pattern 16 "looks" at the target









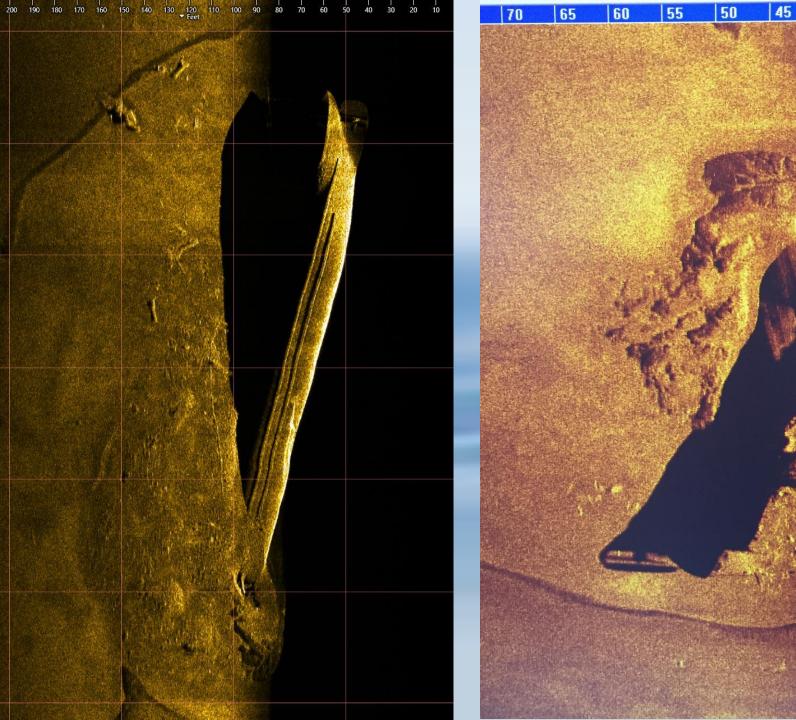


#### <u>Ohio</u>

Length: 202 ft Width: 35 ft Built: 1873, John F. Squires Lost: 1894, collision off Presque Isle, MI.

Design: Wooden Bulk Carrier







# Great Lakes Research Center Michigan Technological University





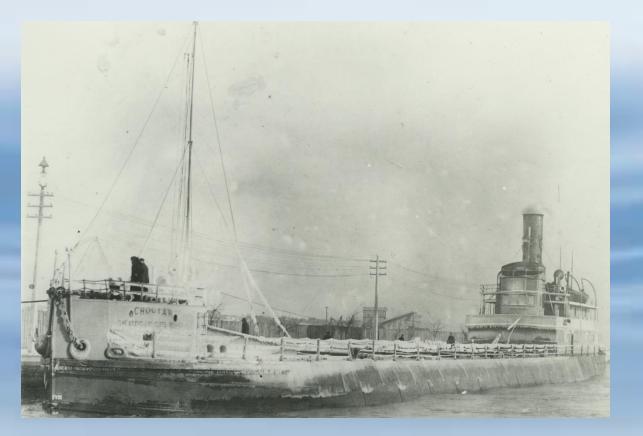


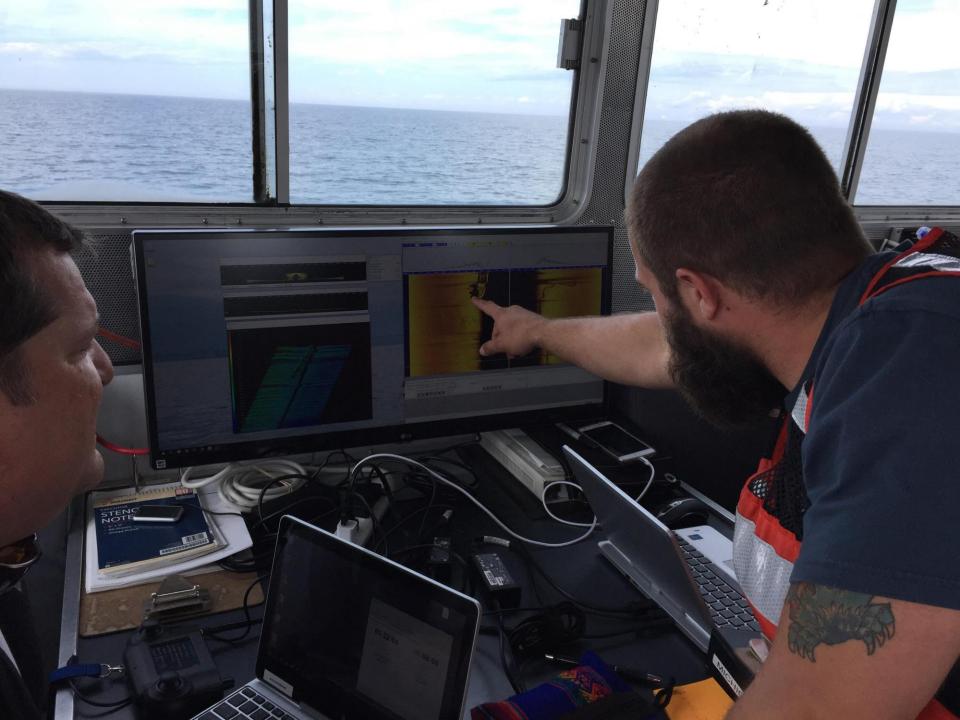
#### **Choctaw**



Design: Bulk Carrier Semi-Whaleback Straight-back Monitor-Style

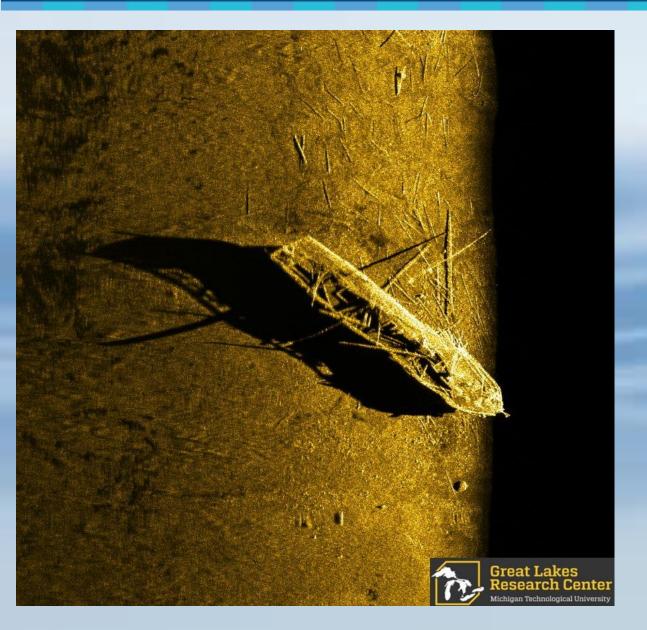












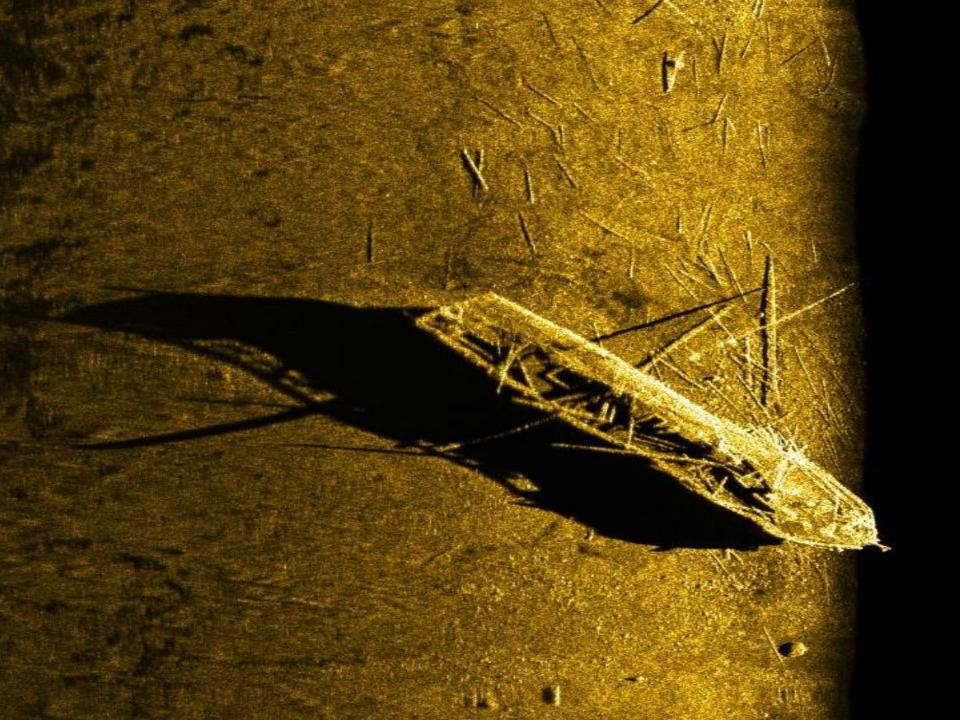
#### <u>John J. Audubon</u>

Depth: 170 ft Length: 148 ft Width: 26 ft Built: 1854 Lost: 1854, collision

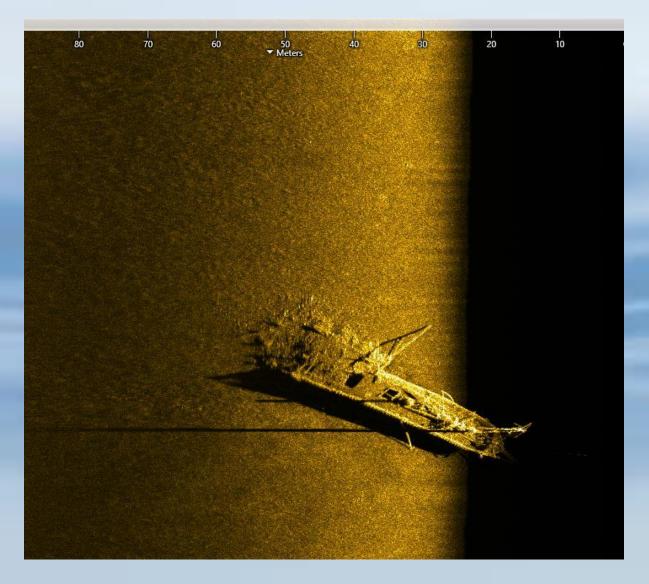
Main Features: Masts/Rigging Rail Iron

#### **Design: Canal Schooner**









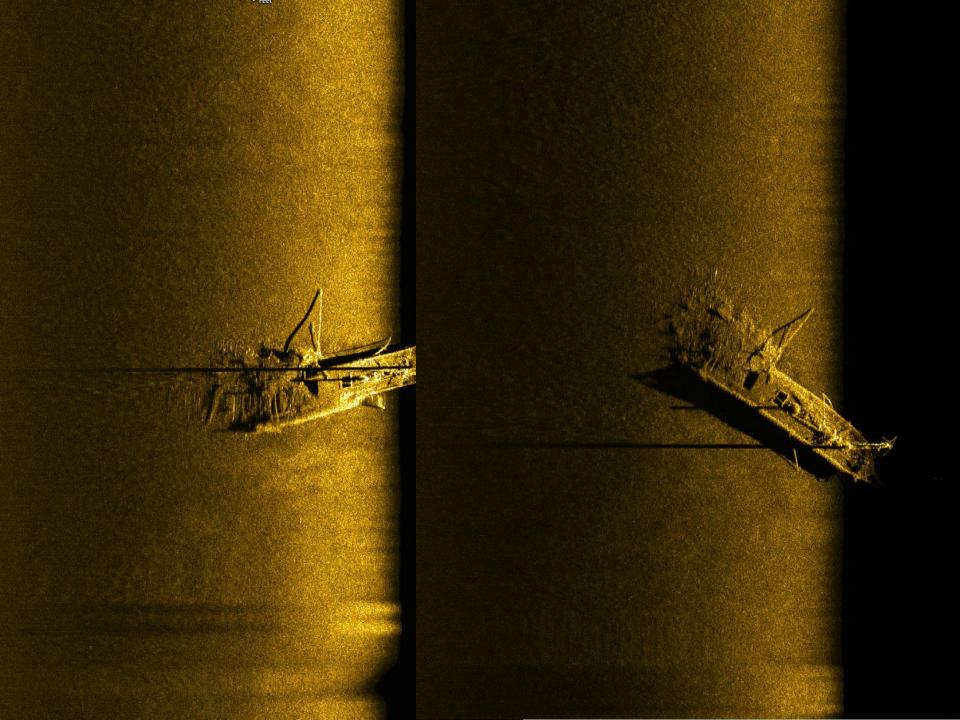
#### Туро

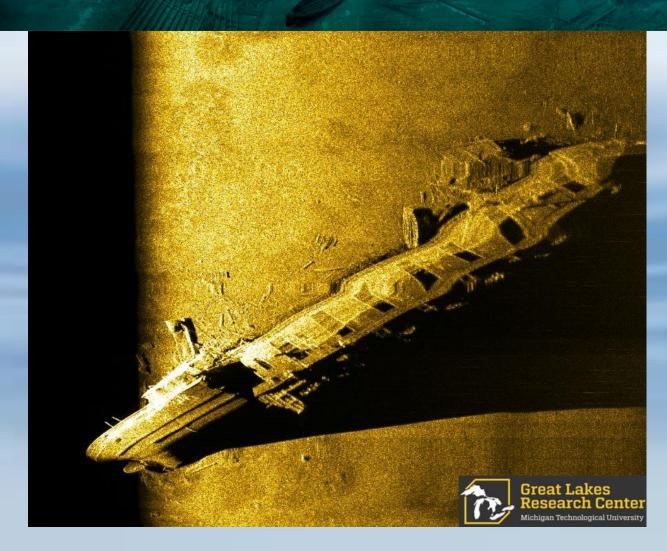
Depth: 160 ft Length: 137 ft Width: 26 ft Built: 1873 Lost: 1899, collision

Main Features: Fore Mast Upright Rigging Smashed Stern Coal









#### <u>Norman</u>

Depth: 205 ft Length: 296 ft Width: 40 ft Built: 1890 Lost: 1895, collision

Main Features: Masts/Rigging Rail Iron Yawl Boat

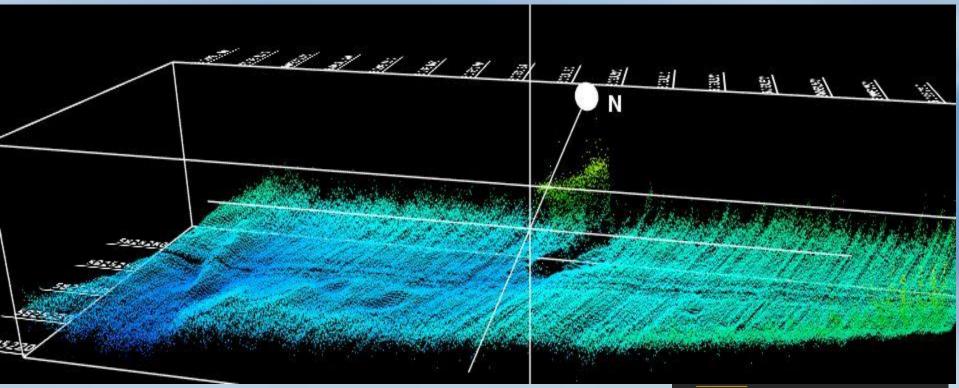


# Where do we go from here ?



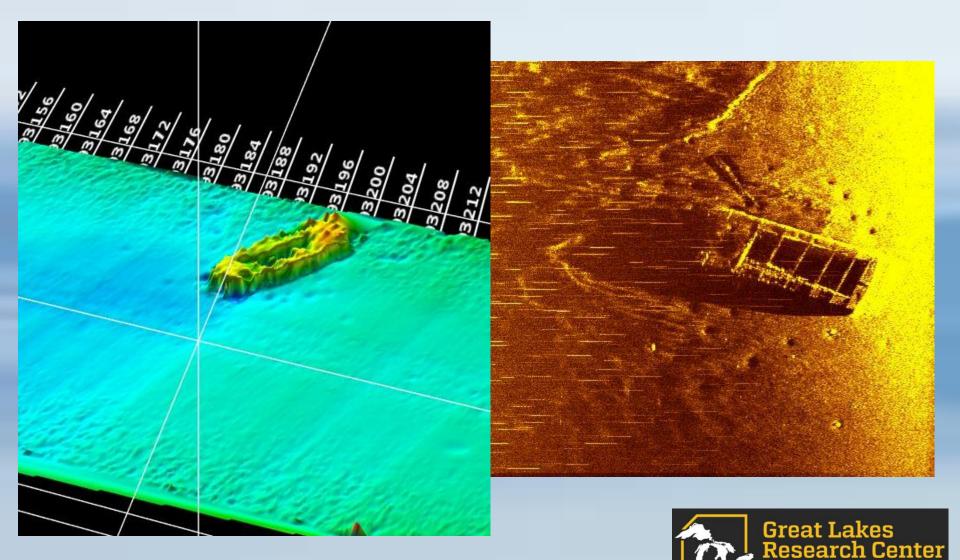
# **Three-Dimensional**

- 3-D Bathymetry
- Every point in the cloud (x,y,z) coordinates





## Sunk Wood Barge – late 1800's



Michigan Technological University

# ASV Global C-Worker 5



- Length X Beam X Draft: (5.5 m X 1.7m X 0.9m)
- Weight = 1900 kg
- Propulsion: Direct Drive Diesel: 57 hp
- Endurance: Up to 5 Days at 7 kts



## C-Worker 5

