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DESIGN AND SIMULATION OF FUZZY INFERENCE BASED MULTIPLE PID CONTROLLERS FOR 6-DOF UNMANNED UNDERWATER VEHICLE

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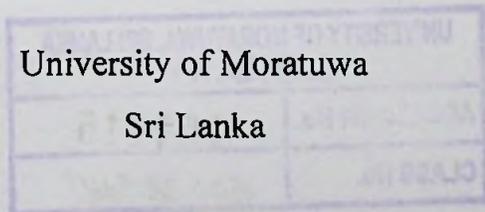
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Thesis submitted in partial fulfillment of the requirements for the degree Master of
Science in Electronics and Automation



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Department of Electronics and Telecommunication Engineering



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January 2014

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DECLARATION

I declare that this is my own work and this thesis does not incorporate without acknowledgement any material previously submitted for a Degree or Diploma in any other University or institute of higher learning and to the best of my knowledge and belief it does not contain any material previously published or written by another person except where the acknowledgement is made in the text.

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The above candidate has carried out research for the Master's thesis under my supervision.

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ABSTRACT

Design and Simulation of Fuzzy Inference Based Multiple PID Controllers for 6-DOF Unmanned Underwater Vehicle

Keywords: PID, fuzzy, inference, multiple controllers, UUV, unmanned, underwater vehicle

Unmanned underwater vehicles are currently being utilised for scientific, commercial and military underwater applications. These vehicles require autonomous guidance and control systems in order to perform underwater tasks. Modelling, simulation and control of these vehicles are still major active areas of research and development.

This thesis explores the design of a control system for a 6-Dof unmanned underwater vehicle. The thesis consists of two phases; the first involves the design of three single decoupled PID controllers for surge, yaw and depth. Then it is shown that it is not possible to cover the entire range of operations of UUV using only single controller by simulation using MATLAB SIMULINK. The second phase is concerned with the design of multiple PID controllers covering the entire range of UUV operation, as well as the fuzzy inference based supervisor design to switch between the different controllers as the operations conditions vary.

The design of the PID controllers are based on MATLAB PID tuning algorithms which is a robust response time tuning algorithms that allows for faster design process with robust gain values. It is shown that these new tuning methods as well as graphical tuning interface overcome the adhoc and time consuming process of finding the PID gains. Further it is shown that fuzzy gain scheduling using fuzzy inference mechanism is a valid method for controlling a UUV with nonlinear dynamics.

It can be concluded that new tools such as MATLAB tuning algorithms and Fuzzy toolbox allows for fast and accurate design of controllers for highly complex systems as well as the viability of fuzzy inference multiple controllers as a method for UUV control with desired response characteristics. Finally the author recommends an actual vehicle implementation and testing as future work to be carried out.

ACKNOWLEDGMENTS

The author wishes to thank the faculty of the Department of Education, University of the Philippines Diliman, for their support and encouragement during the preparation of this manuscript. Special thanks are due to the author's advisor, Dr. [Name], for his guidance and criticism. The author also wishes to thank the members of the Department of Education, University of the Philippines Diliman, for their support and encouragement during the preparation of this manuscript.

A special thanks is due to the Department of Education, University of the Philippines Diliman, for the support and encouragement during the preparation of this manuscript. The author also wishes to thank the members of the Department of Education, University of the Philippines Diliman, for their support and encouragement during the preparation of this manuscript.

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To my parents and teachers

The author wishes to thank the members of the Department of Education, University of the Philippines Diliman, for their support and encouragement during the preparation of this manuscript.

ACKNOWLEDGMENTS

The research project within the Master of Science degree program provides a great opportunity to apply the engineering knowledge gained through the taught modules to a real world scenario. During this period of research I gained vast amount of knowledge and practice with the support of numerous parties. Therefore I would like to thank them all for the successful completion of the project.

First and foremost I wish to convey my sincere gratitude to Prof. Rohan Munasinghe, course coordinator of the Master in Science in Electronics and Automation Engineering and my thesis supervisor. He gave the knowledge on control theories which encouraged me to pursue a research in control related area. As my supervisor he continuously encouraged and guided me to the successful, completion of the research project.

I would like to thank Dr. Ajith Pasqual, Head of the Department of Electronic and Telecommunication Engineering, for leading us with the supporting hand.

I would also thank Prof. Dev Ranmuthugala of Australian Maritime College who introduced me to the idea of unmanned underwater vehicles and encouraged me to pursue the master's thesis in relation to that field.

Finally I would like to thank all the members of the academic staff, for sharing their knowledge and previous experiences with us, in successful completion of the project, all the non-academic staff members and our batch mates for giving me support in numerous ways.

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LIST OF ABBREVIATIONS

Abbreviation	Description
AUV	Automated Underwater Vehicle
CB	Centre of Buoyancy
CG	Centre of Gravity
CGS	Conventional Gain Scheduling
DOF	Degrees Of Freedom
FGS	Fuzzy Gain Scheduling
GUI	Graphical User Interface
GUIDE	GUI Development Environment
NED	North-East-Down
NPS	Naval Postgraduate School
MSS	Marine systems Simulator
PD	Proportional Derivative
PI	Proportional Integral
PID	Proportional Integral Derivative
ROV	Remotely Operated Vehicle
UAV	Unmanned Aerial Vehicle
URV	Underwater Recovery Vehicle
UUV	Unmanned Underwater Vehicle