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A METHOD TO LOCALIZE AN UNDERWATER OBJECT

STATEMENT OF GOVERNMENT INTEREST

[0001] The invention described herein may be manufactured and used by or for the Government of the United States of America for governmental purposes without the payment of any royalties thereon or therefor.

CROSS REFERENCE TO OTHER PATENT APPLICATIONS

[0002] None.

BACKGROUND OF THE INVENTION

(1) Field of the Invention

[0003] The invention relates to a system and a corresponding method for detecting a location of an underwater object using sound navigation and ranging (SONAR) arrays.

(2) Description of the Related Art

[0004] A position of an underwater source is detectable by using SONAR technology. A linear array of hydrophones is utilized to detect these sources. Because of the linear array geometry, an angle of signal arrival can be determined, but one does not know the range to the source or the position of the signal other than on the surface of a cone. Due to the conical

shape of the coverage area of the SONAR signal, it is termed as the cone of coverage of the SONAR array.

[0005] A surface vessel and an underwater vessel may include SONAR arrays to determine position of objects of interest within the water in close range. Each SONAR array may include a plurality of sensor elements or hydrophones. Time delays between signal arrivals at sensor elements along the array allow determination of an angle of arrival. However, there may remain ambiguity regarding exact location of the object with respect to the cone of coverage. By using a single SONAR element or a plurality of SONAR elements in an array, it may not be possible to localize an object within close range of the vessel.

SUMMARY OF INVENTION

[0006] A system and a corresponding method for localizing an underwater object is provided. Signals are received from a source at a first towed array and a second towed array. These towed arrays are positioned at different depths underwater. The estimated location of the source within a near field can be found based on overlapping cones of the received signals.

[0007] In further detail, a first array of SONAR elements and a second array of SONAR elements are towed by a vessel. The first and second towed arrays are vertically separated, with the

first array located above the second array. Further, the first and second arrays are linearly separated along a direction of travel of the vessel. A third array is positioned on or near the vessel.

[0008] Acoustic emissions from an underwater object or source are detected by elements of the first towed array and the second towed array. Using beamforming, each of these arrays can resolve the position of the object to a cone of coverage having a conical angle. The object position can be further defined by the intersection of the first array coverage cone and the second array coverage cone. If the source is also detected by the SONAR elements of a third array, a bearing angle and a depression/elevation (DE) angle toward the source may be obtained from the third array. A unique point on the estimated contour of the intersection of the two cones that corresponds to the bearing angle and DE angle detected by the third array provides the location of the source.

[0009] By using signals detected at two vertically separated SONAR arrays, it is possible to localize to obtain range, depth, and bearing of an underwater object. By using two arrays instead of one along with a third array at the vessel, ambiguity regarding the exact location of the source is removed. The parallel towed arrays may be used during vessel navigation to locate any objects of interest in close proximity to the vessel.

BRIEF DESCRIPTION OF THE DRAWINGS

[0010] Features of illustrative embodiments may be understood from the accompanying drawings in conjunction with the description. The elements in the drawings may not be drawn to scale. Some elements and/or dimensions may be enlarged or minimized for the purpose of illustration and understanding of the disclosed embodiments wherein:

[0011] **FIG. 1** is a view of two towed arrays used to estimate a position of an underwater object proximal to a vessel towing the arrays.

[0012] **FIG. 2** shows an example flow-chart for estimation of the position of the underwater object based on signals received at the two towed arrays.

DETAILED DESCRIPTION OF THE INVENTION

[0013] The following description relates to a system and corresponding method for detecting the location of an underwater source using two towed SONAR arrays. The system, including the SONAR arrays towed from a vessel, as used for detection of location of an underwater object proximal to the vessel, is shown in **FIG. 1**. An example method for detection of position of the underwater object based on signals detected by the towed SONAR arrays is shown in **FIG. 2**.

[0014] **FIG. 1** depicts an example schematic of a setup **100** for detection of location of an underwater source **102** proximal to a vessel **104**. The underwater object **102** is submerged in water **106** under the surface **108** of a water body such as an ocean. A first tow line **110** may be coupled to the vessel **104** to support a first array **112** and a second array **114**. Each of the first array **112** and the second array **114** may be provided underwater in the same vertical plane with the vessel **104**. As an example, the vertical plane shared by the first array **112**, the second array **114**, and the vessel **104** is the x-z axis of the coordinate system **116**. The vessel travels forward in the direction of positive x-axis and the depth of water increases in the direction of the positive z-axis. A distance to port or starboard is along the y-axis.

[0015] Each of the first array **112** and the second array **114** includes a plurality of SONAR elements **118** configured with sensors for receiving acoustic signals from underwater objects. The elements **118** are linearly arranged along the arrays parallel to the x-axis. The first array **112** and the second array **114** may be parallel to each other with the second array **114** positioned vertically below the first array **112** with a distance (along the z axis) between the two arrays. Tow depth of the two arrays may be different (such as second array **114** having different buoyancy parameters than first array **112**) to enable the two arrays to be

vertically displaced with the second array **114** being at a greater depth (within water) relative to the first array **112**. In this example, the two arrays are being towed by a vessel which may be a surface vessel. In alternate examples, the vessel may be a submarine with one array towed above the submarine (at a shallower depth relative to the submarine) and another array towed below the submarine (at a deeper depth relative to the submarine).

[0016] A first phase center of the first array **112**, as shown by point **P1**, may be assumed to be an origin $(0, 0, 0)$ of the coordinate system **116**. A second phase center of the second array **114**, as shown by point **P2**, may be shifted along the x-axis and the z-axis relative to **P1**. The coordinates for **P2** are defined as $(\Delta r, 0, \Delta z)$ with Δr corresponding to the difference in range and the Δz corresponding to the difference in depth relative to **P1**. A first cone **120** corresponding to the first array **112** and a second cone **122** corresponding to the second array **114** intersect in an ellipse **123**. Source **102** will be located at a point on the ellipse **123**. In this example, the range of the source is parallel to the x-axis, hence the dimension along the x-axis is represented by the variable **r**.

[0017] A third sonar array **124** is positioned at the vessel **104** and the third array **124** is able to detect a bearing angle

and a depression/elevation angle to the source **102**. Arrow **126** indicates this detection path.

[0018] The setup **100** further includes a controller **128**. The controller **128** may be positioned at the vessel **104** or at a remote location communicatively connected to the vessel **104** through a wireless network. The controller **128** is configured as a conventional microcomputer including a microprocessor unit, input/output ports, read-only memory, random access memory, keep alive memory, a controller area network (CAN) bus, etc. The controller **128** receives input data from the various elements of the SONAR arrays, processes the input data, and estimates the position of an underwater object close by in response to the processed input data based on instruction or code programmed therein corresponding to one or more routines. A method for estimation of the position of the underwater object based on signals received at the two towed arrays is described in **FIG. 2**.

[0019] In this way, the system of **FIG. 1** provides for a first array **112** of SONAR elements towed underwater by the vessel **104**, a second array **114** of SONAR elements towed underwater by the vessel, the second array at a greater depth relative to the first array, a third SONAR array **124** at the vessel, and an underwater object **102** positioned at an intersection of a first cone **120** of coverage of the first array and a second cone **122** of coverage of the second array proximal to the vessel.

[0020] **FIG. 2** shows a method **200** for estimation of a position of an underwater object (such as object **102** in **FIG. 1**) based on signals received at two arrays towed by a vessel (such as vessel **104** of **FIG. 1**) proximal to the source, in addition to a third array (such as third array **124** of **FIG. 1**) at the vessel. Method **200** will be described in reference to the systems described herein and with regard to **FIG. 1**, but it should be understood that similar methods may be applied to other systems without departing from the scope of this disclosure. Method **200** is carried out by a control system, and may be stored in non-transitory memory. Instructions for carrying out method **200** is executed by the control system in conjunction with signals received from SONAR arrays.

[0021] At **202**, signals are received from each of a first SONAR array (such as first array **112** in **FIG. 1**) and a second SONAR array (such as second array **114** in **FIG. 1**). The vertically displaced arrays include a plurality of sensors to detect presence of sources proximal to the vessel. In the presence of such a proximal source, a first cone (such as first cone **120** in **FIG. 1**) corresponding to the first array and a second cone (such as second cone **122** in **FIG. 1**) corresponding to the second array intersect at the source. In further detail, the controller **128** resolves these cones as is known in the art by the delayed signal outputs of the sensors in the array.

[0022] At 204, coordinates of points on a surface of each of the first cone and the second cone are estimated. Points on a surface of the first cone are given by equation 1:

$$y^2 + z^2 = r^2 \tan^2 \gamma_1 \quad (1)$$

where γ_1 is the opening angle of the first cone receiving signal from the source, and y, z, r are variables. Points on a surface of the second cone is given by equation 2:

$$y^2 + (z - \Delta z)^2 = (r - \Delta r)^2 \tan^2 \gamma_2 \quad (2)$$

where γ_2 is the opening angle of the second cone 122 receiving a signal from the source, and y, z, r are variables.

[0023] Equations 1 and 2 can be solved for z to obtain equation 3 as a function of r for the intersection of the two cones, as follows:

$$z = f(r) = ar^2 + br + c \quad (3)$$

where,

$$a = \frac{\tan^2 \gamma_1 - \tan^2 \gamma_2}{2\Delta z}, \quad b = \frac{\Delta r \tan^2 \gamma_2}{\Delta z}, \quad c = \frac{\Delta z^2 - \Delta r^2 \tan^2 \gamma_2}{2\Delta z}.$$

[0024] At 206, a contour is formed at the intersection of the first cone and the second cone. Using the equations 1-3, equation 4 is obtained for y as a function of r and z .

$$y = \pm \sqrt{r^2 \tan^2 \gamma_1 - z^2} \quad (4)$$

[0025] Equation 4 provides a set of points on a contour which is the intersection of the first cone and the second cone. The

source is located on this contour. Based on the current system in use, such as the location of the boat, properties of the first, second, and third arrays, a range of boundary coordinates can be deduced for the contour. As an example, minimum and maximum values of range, depth, bearing angle, and depression/elevation angle are pre-calibrated and obtained from a control system memory.

[0026] At **208**, a bearing angle and a depression/elevation angle of the source as detected by the third sonar array positioned at the vessel is obtained. In one example, β_{shp} and DE_{shp} represent the bearing and depression/elevation (DE) angle of the source as obtained from the third sonar array on the ship. The location of the phase center of the third sonar array in a coordinate system (such as coordinate system **116** of **FIG. 1**) is given by $(\Delta r_s, 0, \Delta z_s)$. The β_{shp} and DE_{shp} obtained by the third sonar array provide a unique point on the contour which corresponds to the location of the source.

[0027] At **210**, the location of the source is obtained by applying bearing and depression/elevation angles (β_{shp} and DE_{shp}) from the third array to the contour.

[0028] A triangle is formed with the locations of the source, a projection of the source onto a horizontal plane, and a phase center of the third sonar array as apex points. The location of

the phase center of the third sonar array is in a vertical plane that is rotated through the angle β_{shp} .

[0029] For the points on the contour, corresponding bearing and depression/elevation angles relative to the third array are given by equations 5 and 6.

$$\beta_{shp} = \tan^{-1} \frac{y}{r - \Delta r_s} \quad (5)$$

$$DE_{shp} = \tan^{-1} \frac{(z - \Delta z_s) \cos \beta}{r - \Delta r_s} \quad (6)$$

[0030] In this way, a set of possible source locations defined by range, depth, distance to port or starboard, bearing angle, and DE angle is obtained. To identify a unique solution within that set, the bearing angle and DE angle obtained from the third array is converted to a corresponding cone angle. The cone angle at the third sonar array is computed to each of the possible source locations on the contour. The cone angle (γ_{shp}) is given by equation 7.

$$\gamma_{sph} = \cos^{-1}(\cos \beta_{shp} \cdot \cos DE_{shp}) \quad (7)$$

[0031] The intersection of the cone angle with the contour provides the location of the source. The location of the source is defined by range, depth, bearing angle, and DE angle to the source.

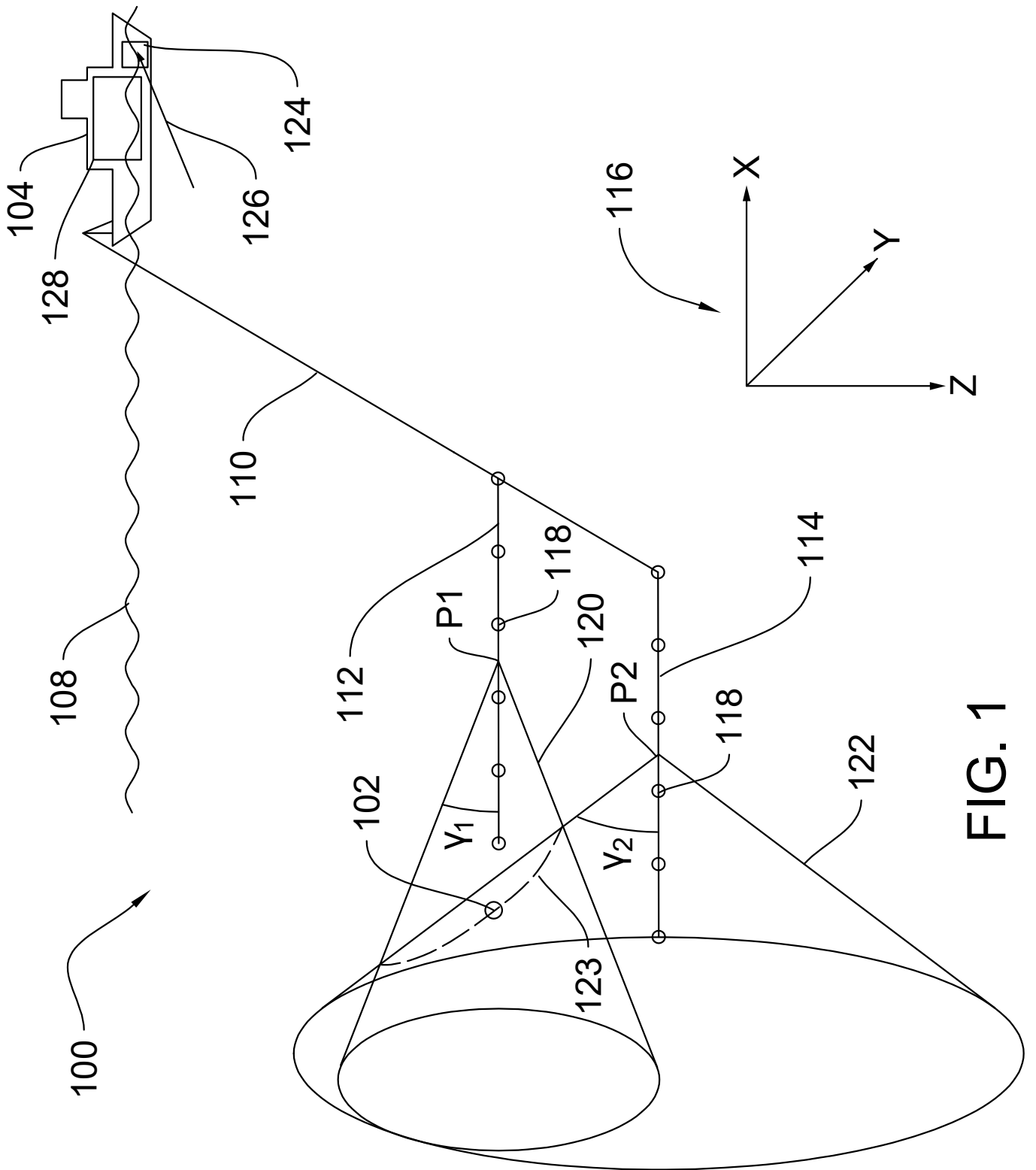
[0032] In this way, a first signal is received on a first linear sonar array resolving to a first cone of signal source locations, the same signal is received on a second linear sonar array resolving to a second cone of signal source locations, the same signal is received at a third sonar array, and a location of the underwater source in a near-field is estimated based on the information received at the three arrays. By using two parallel towed arrays, in addition to a third array at the vessel, it is possible to determine the location of an underwater object in close proximity to a vessel.

[0033] It will be understood that many additional changes in the details, materials, steps and arrangement of parts, which have been herein described and illustrated in order to explain the nature of the invention, may be made by those skilled in the art within the principle and scope of the invention as expressed in the appended claims.

A METHOD TO LOCALIZE AN UNDERWATER OBJECT

ABSTRACT OF THE DISCLOSURE

A method for locating an underwater acoustic source includes using first and second linear arrays to receive signals. These signals can be resolved into intersecting cones and a contour of possible source locations can be estimated. In further embodiments, a third sonar array can receive a bearing and a depression/elevation from a signal. This information can be used with the contour to estimate a source location.



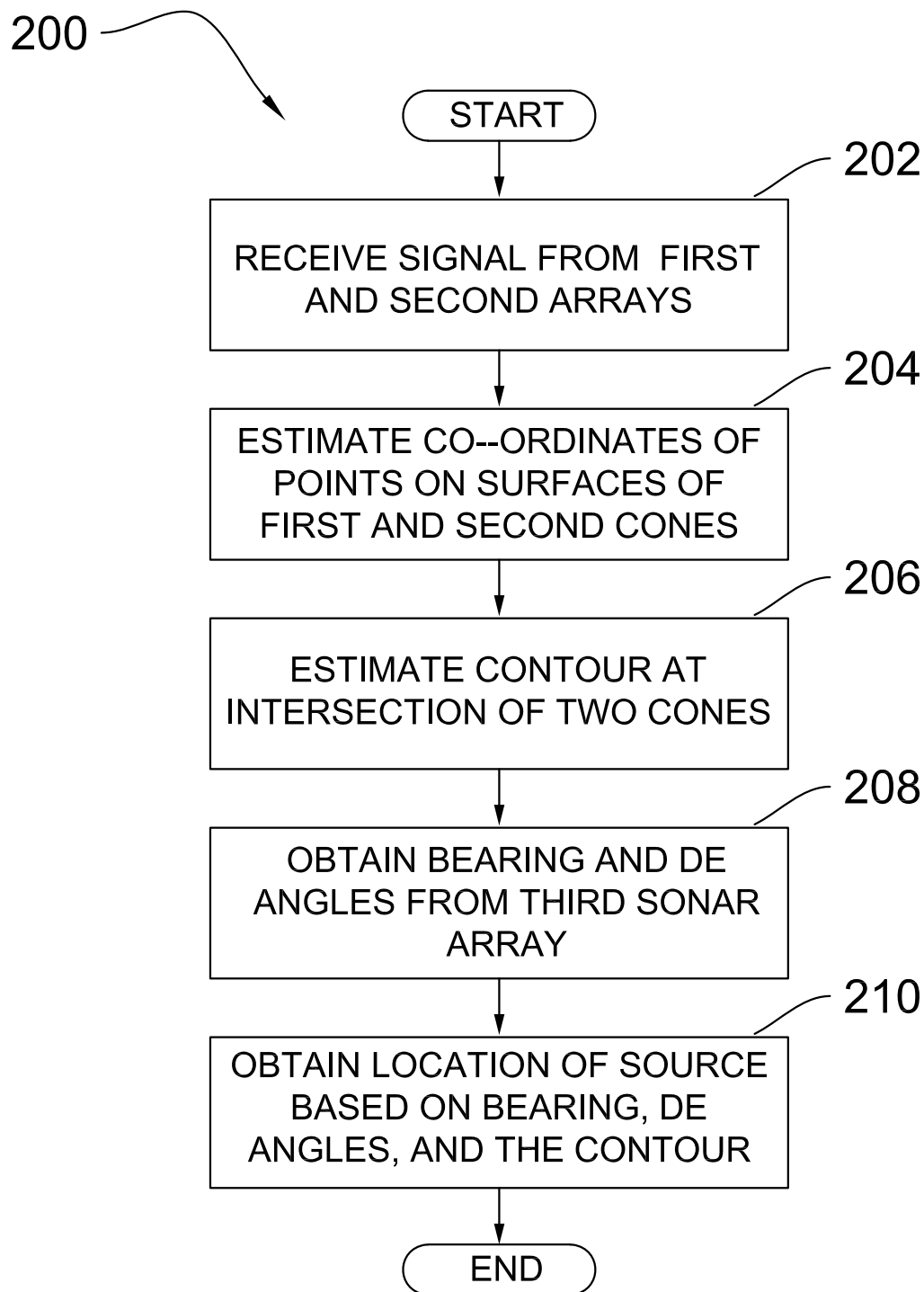


FIG. 2