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ANSER Technologies - UAV Applications

Brad Yelland

**Head of UAV Technology Development
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(with thanks to Dr. Julia Sutcliffe, BAE Systems Australia)

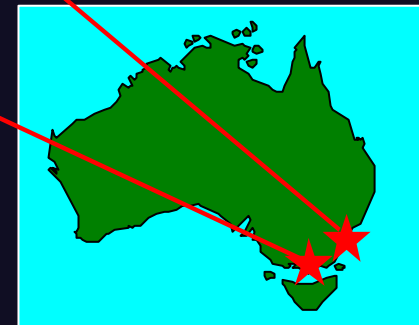
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Report Documentation Page			Form Approved OMB No. 0704-0188		
Public reporting burden for the collection of information is estimated to average 1 hour per response, including the time for reviewing instructions, searching existing data sources, gathering and maintaining the data needed, and completing and reviewing the collection of information. Send comments regarding this burden estimate or any other aspect of this collection of information, including suggestions for reducing this burden, to Washington Headquarters Services, Directorate for Information Operations and Reports, 1215 Jefferson Davis Highway, Suite 1204, Arlington VA 22202-4302. Respondents should be aware that notwithstanding any other provision of law, no person shall be subject to a penalty for failing to comply with a collection of information if it does not display a currently valid OMB control number.					
1. REPORT DATE 02 SEP 2003		2. REPORT TYPE N/A		3. DATES COVERED -	
4. TITLE AND SUBTITLE ANSER Technologies - UAV Applications				5a. CONTRACT NUMBER	
				5b. GRANT NUMBER	
				5c. PROGRAM ELEMENT NUMBER	
6. AUTHOR(S)				5d. PROJECT NUMBER	
				5e. TASK NUMBER	
				5f. WORK UNIT NUMBER	
7. PERFORMING ORGANIZATION NAME(S) AND ADDRESS(ES) BAE Systems Australia				8. PERFORMING ORGANIZATION REPORT NUMBER	
9. SPONSORING/MONITORING AGENCY NAME(S) AND ADDRESS(ES)				10. SPONSOR/MONITOR'S ACRONYM(S)	
				11. SPONSOR/MONITOR'S REPORT NUMBER(S)	
12. DISTRIBUTION/AVAILABILITY STATEMENT Approved for public release, distribution unlimited					
13. SUPPLEMENTARY NOTES See also ADM001676, UAV 2002 Conference & Exhibition., The original document contains color images.					
14. ABSTRACT					
15. SUBJECT TERMS					
16. SECURITY CLASSIFICATION OF:			17. LIMITATION OF ABSTRACT UU	18. NUMBER OF PAGES 22	19a. NAME OF RESPONSIBLE PERSON
a. REPORT unclassified	b. ABSTRACT unclassified	c. THIS PAGE unclassified			

ANSER Background

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- **BAE SYSTEMS Research and Demonstration Programme**
 - **Network Centric Warfare Technologies**
 - **Autonomous Operations Technologies**
- **Element of BAE SYSTEMS Strategic Options Programme**
- **Collaboration between**
 - **BAE SYSTEMS - ATC Sowerby**
 - **University of Sydney - Australian Centre for Field Robotics**
 - **BAE SYSTEMS Australia - Missiles & Decoys**
- **Primary Activities in Australia**
- **Culmination of over 10 years of focused research**



ANSER FOCUS

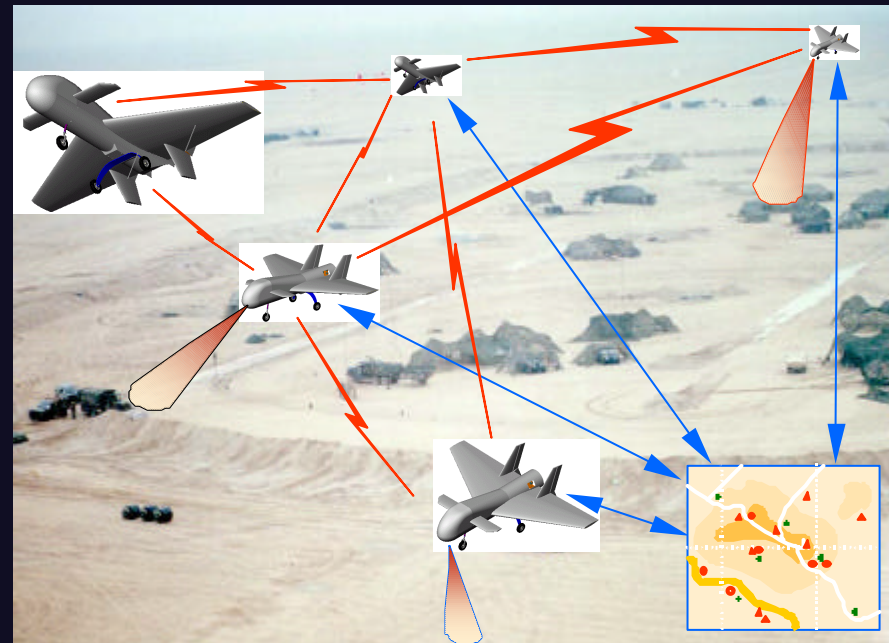
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- **Current Focus (Phase 1)**

- Multi-platform / Multi-sensor Data Fusion
- Multi-Platform Picture Compilation (Situational Awareness)
- Improved Navigation and Target Location accuracy
- GPS Denied Operations

- **Future Focus (Phase 2)**

- Decentralised Control
- Sensor / Platform Co-ordination
- Multi-platform Co-operation

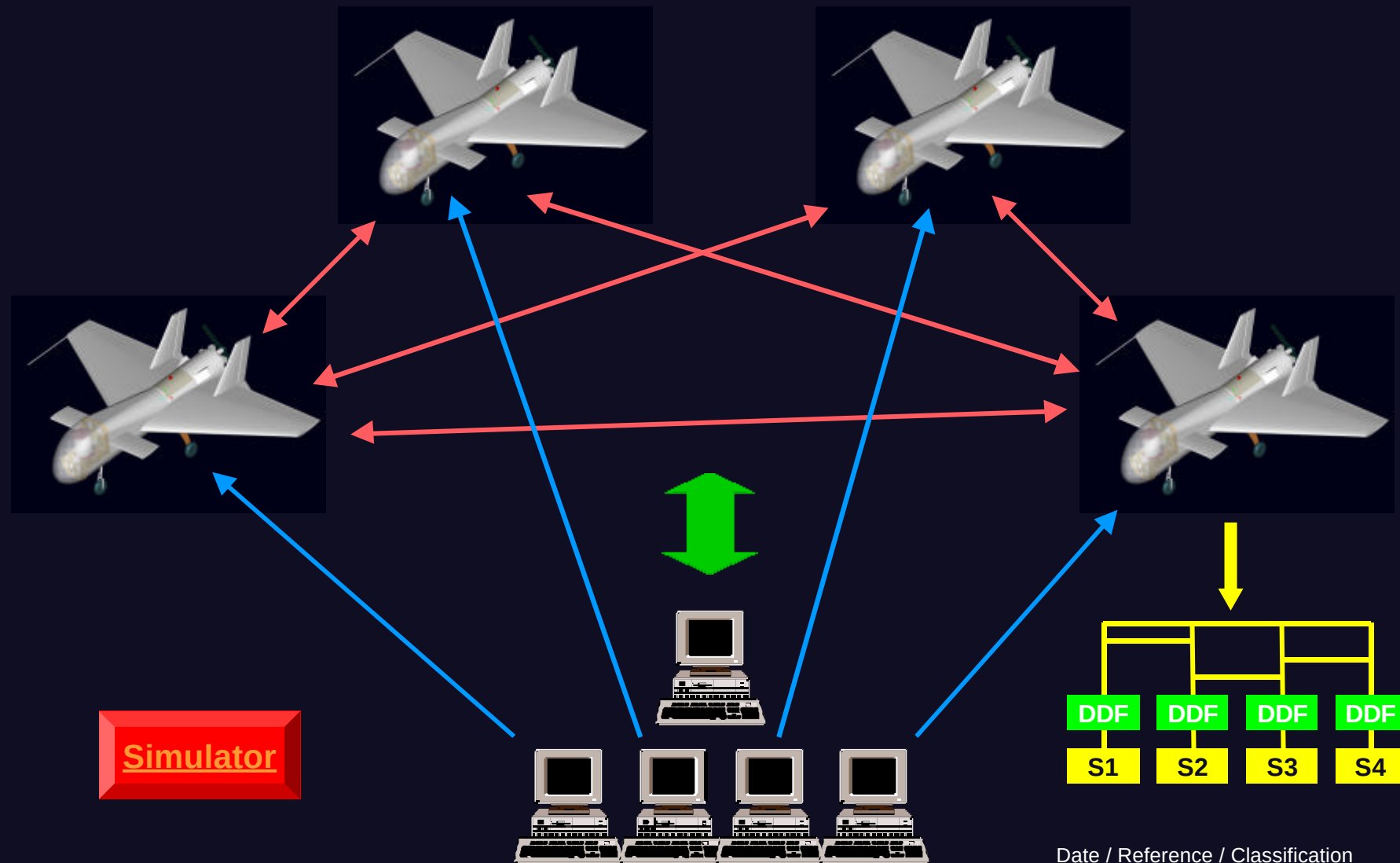


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- **Decentralised Data Fusion (DDF)**
- **Simultaneous Localisation and Map-building (SLAM)**

ANSER Demonstration and Systems

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Focus of this Presentation

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- Achieving Accurate Navigation and Target Location in a GPS Denied Environment through

SLAM

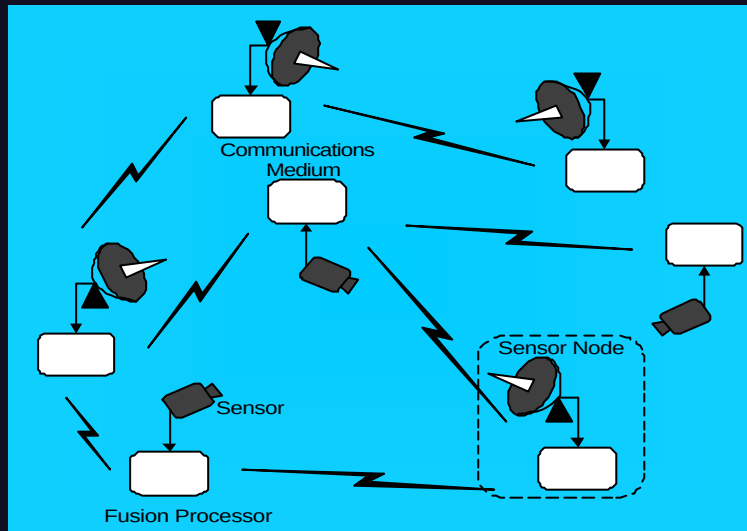
- Single Sensor
- Multi-Sensor

DDF

- Single Platform
- Multi-Platform

What is a DDF system?

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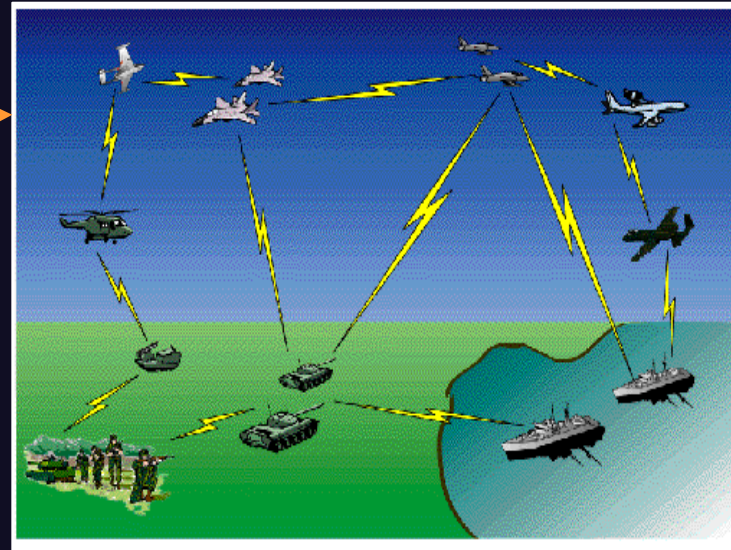


Decentralised system

- network of sensor nodes
- local observations
- communication between neighbouring nodes

Constraints implemented

- no central fusion centre
- no common comms facility
- no global knowledge



Classification

DDF node structure and function

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- Employ Information filter forms:
 - Inverse Covariance (Fisher)
 - Log of probability ratio (Shannon)

Measure Compactness
of Information

Fusion of:

Local observation information

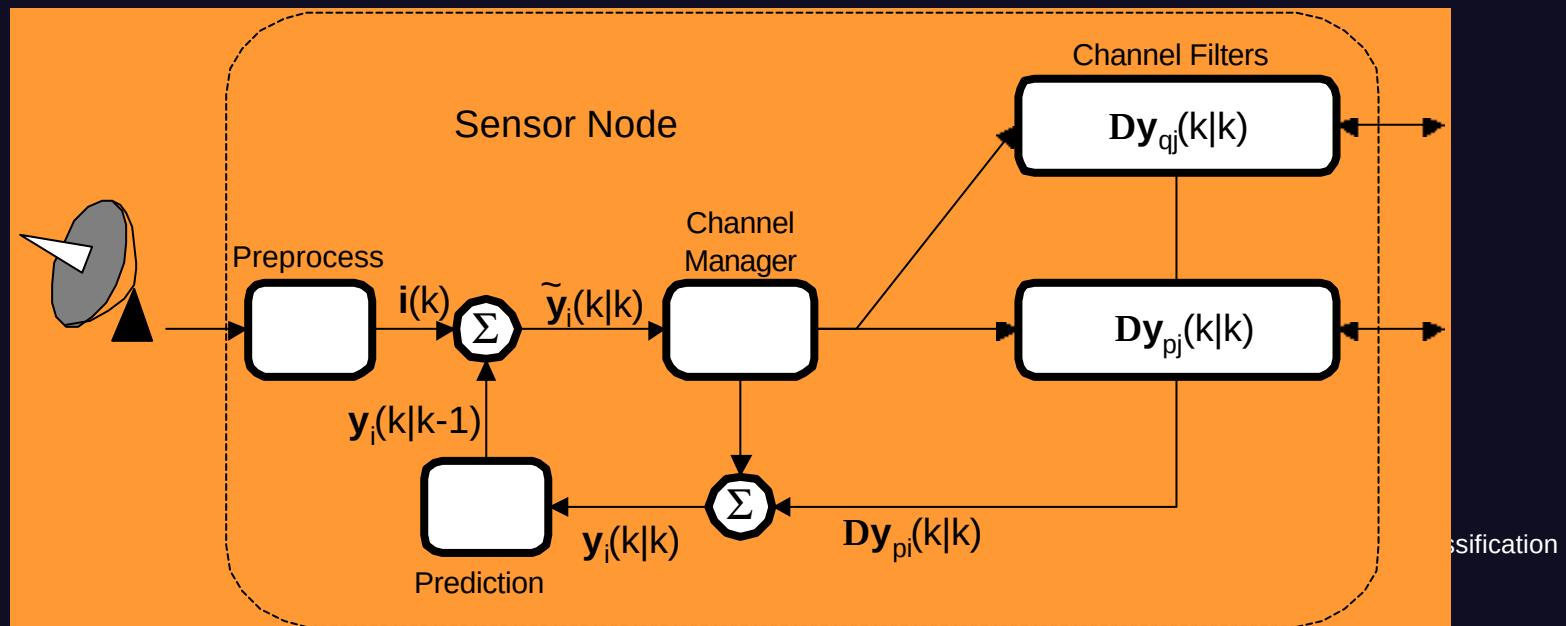
Local prediction information

Communicated information gain

Channels:

Assimilate local information

Communicate information gain.

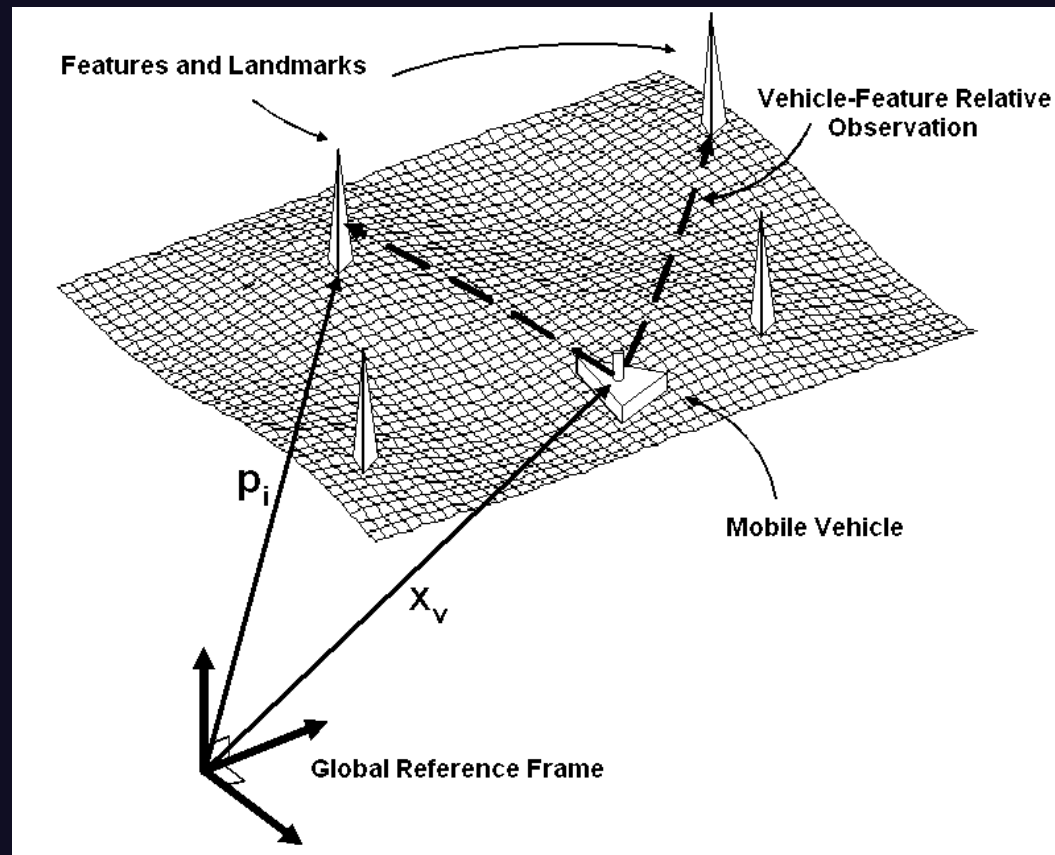


SLAM

Simultaneous Localisation and Map-building

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Problem Structure

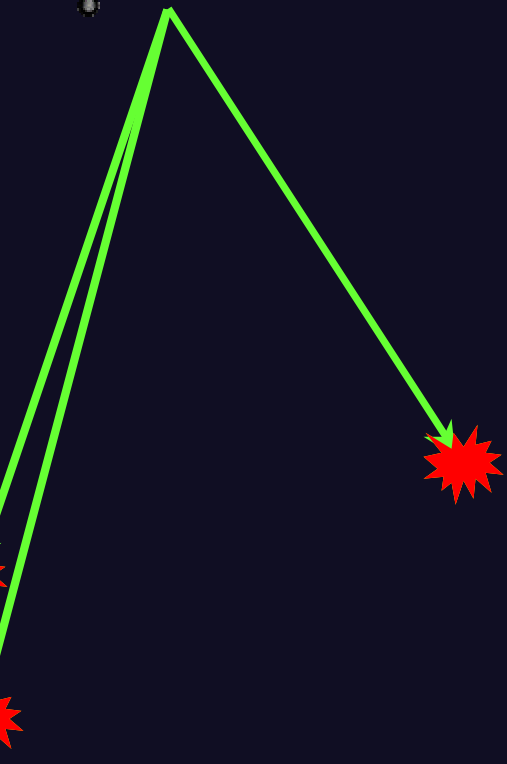


- Unknown location
(no GPS).
- Unknown environment
(no map).
- Build a relative map (of features and targets).
- Use that map to navigate.

Hybrid of two problems:

- target tracking
- map navigation.

Predict



Predict



Re-observe

Correlate



Predict



Re-observe

Correlate

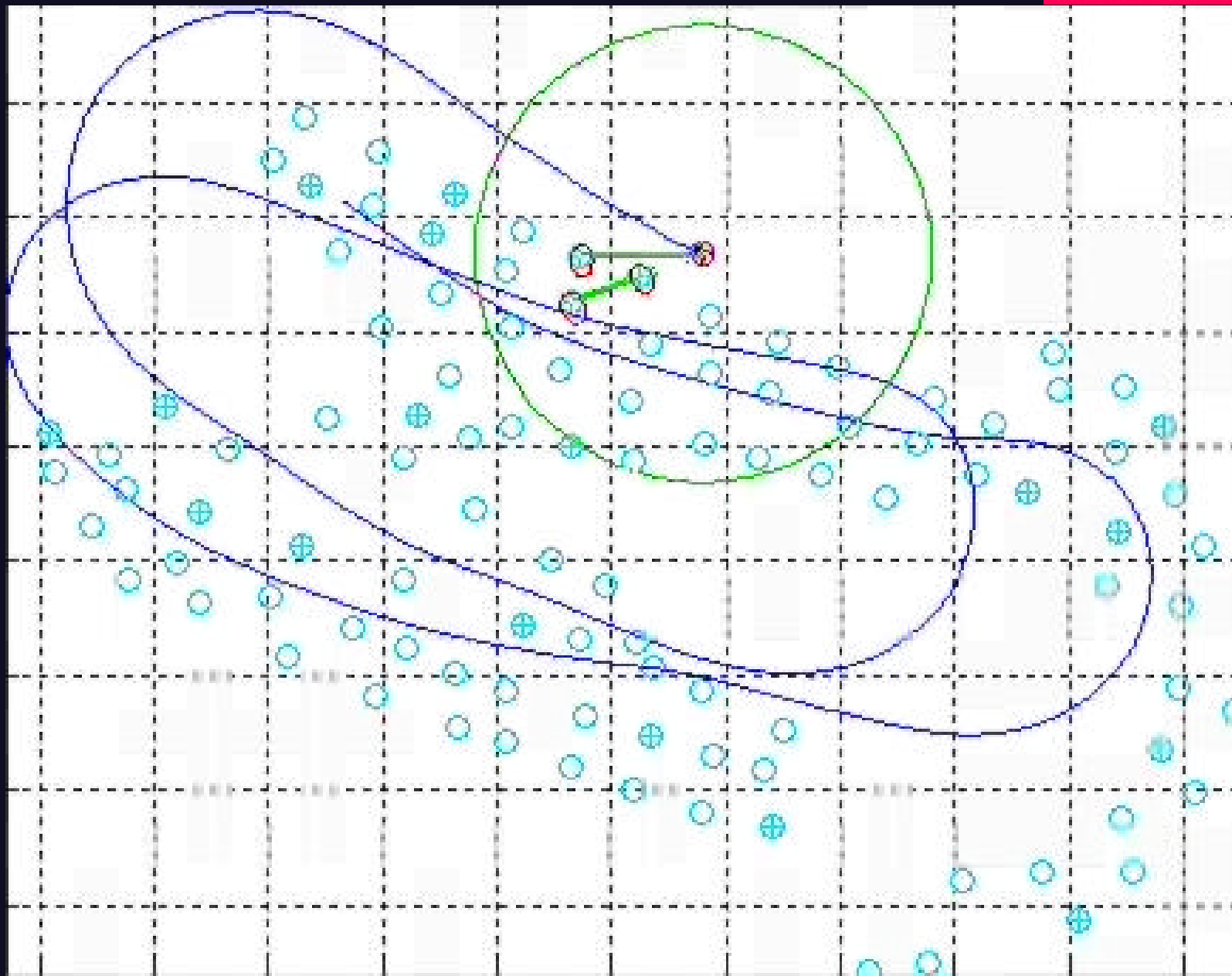


Correlate



SLAM in Flight

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tion

SLAM Performance

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Correlations between landmarks increase monotonically.

The SLAM algorithm can create a perfect relative map of landmarks.

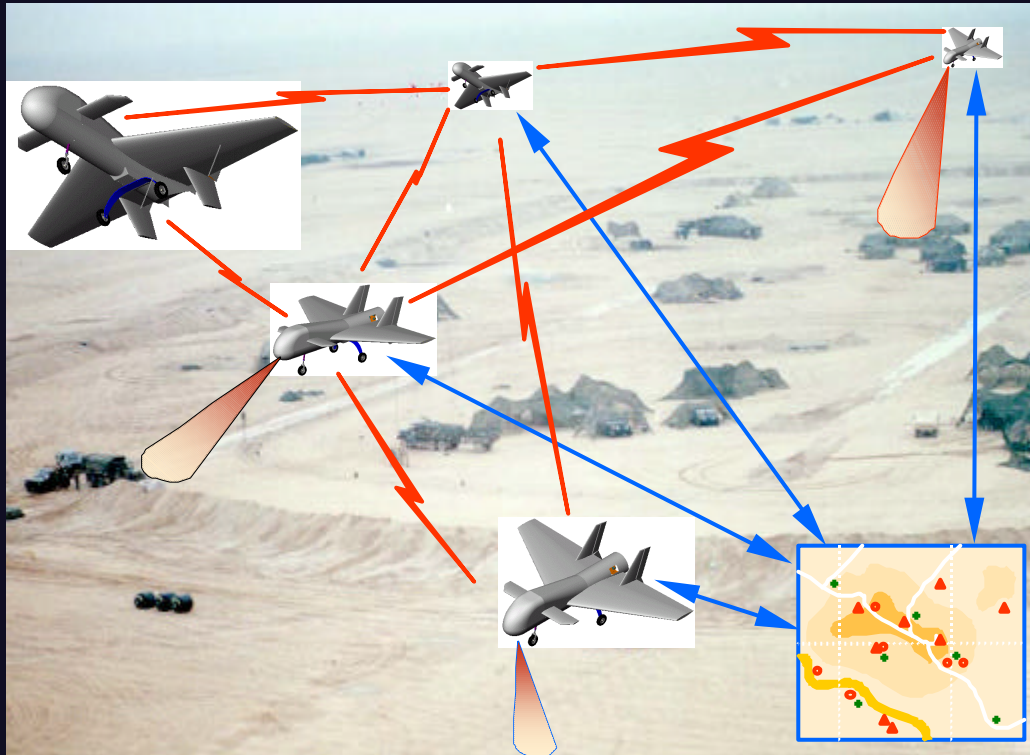
The SLAM algorithm bounds platform pose error.



Reduced Reliance on GPS

Combining DDF with SLAM

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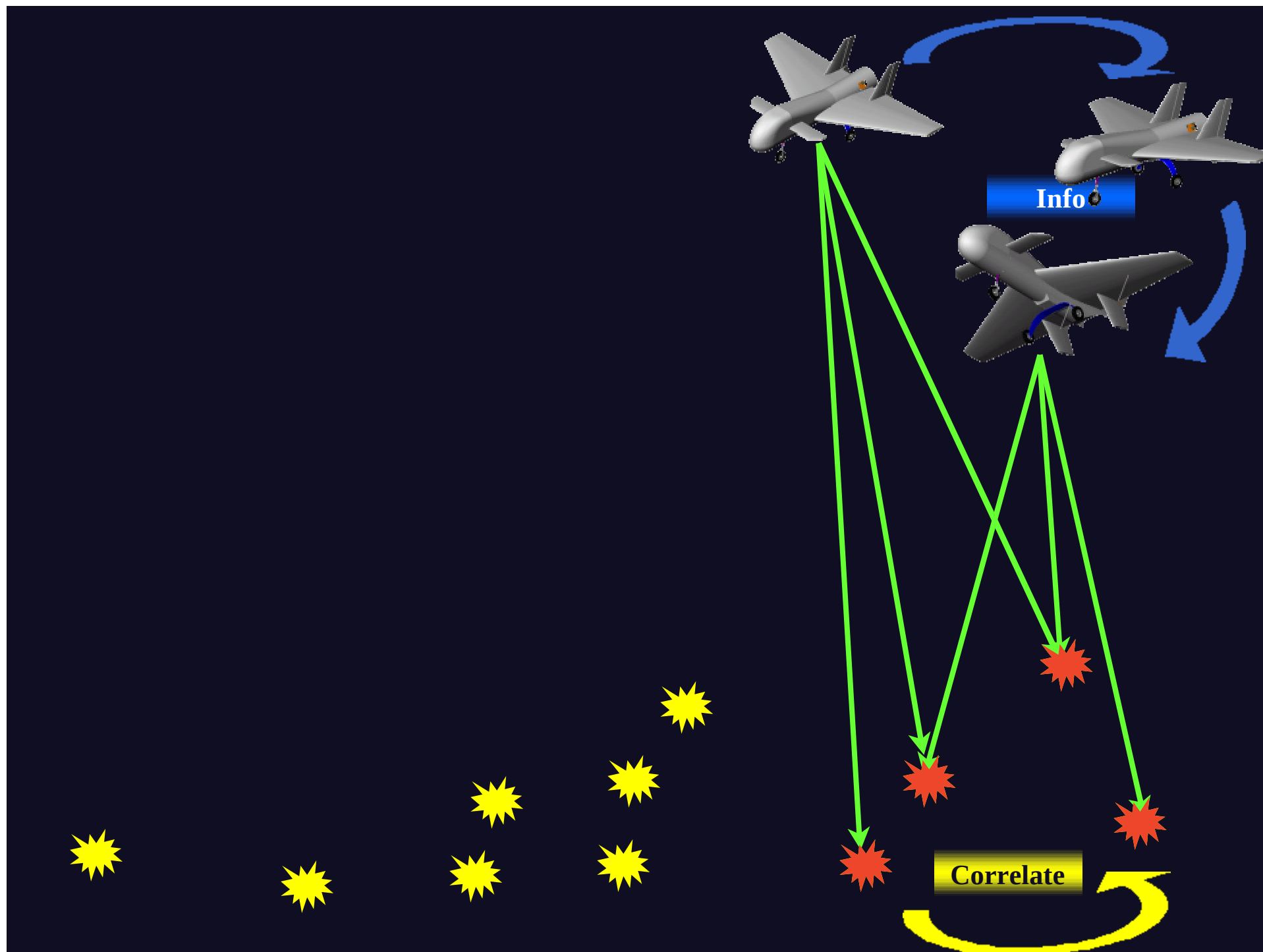
In Information or *decentralised* form, maps can easily be shared between platforms.

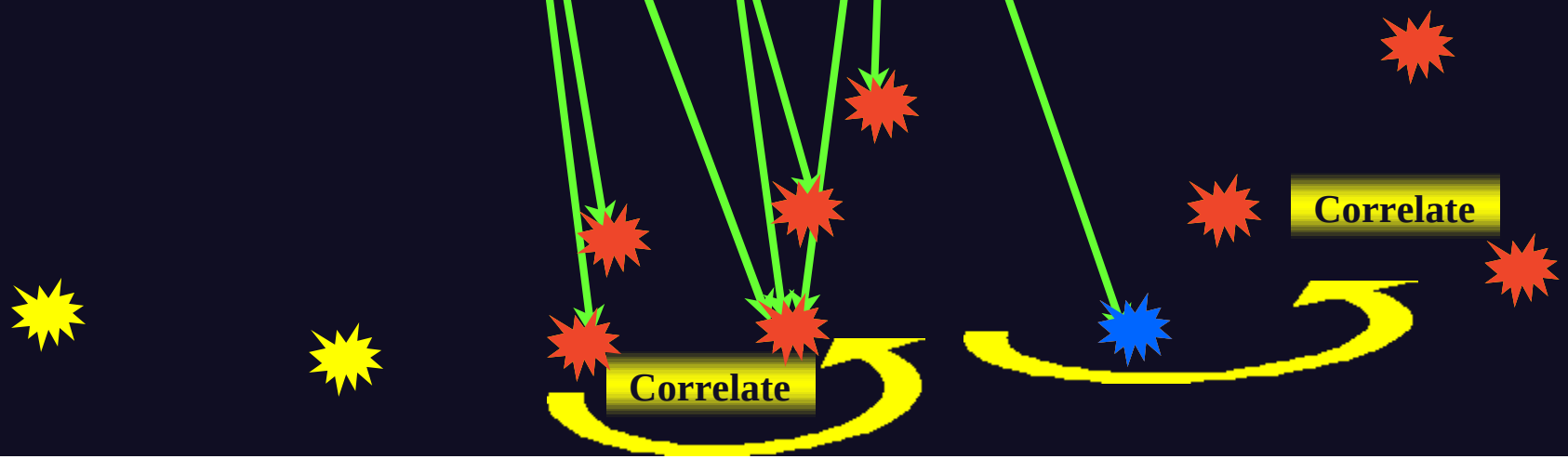
Partial maps can be communicated.

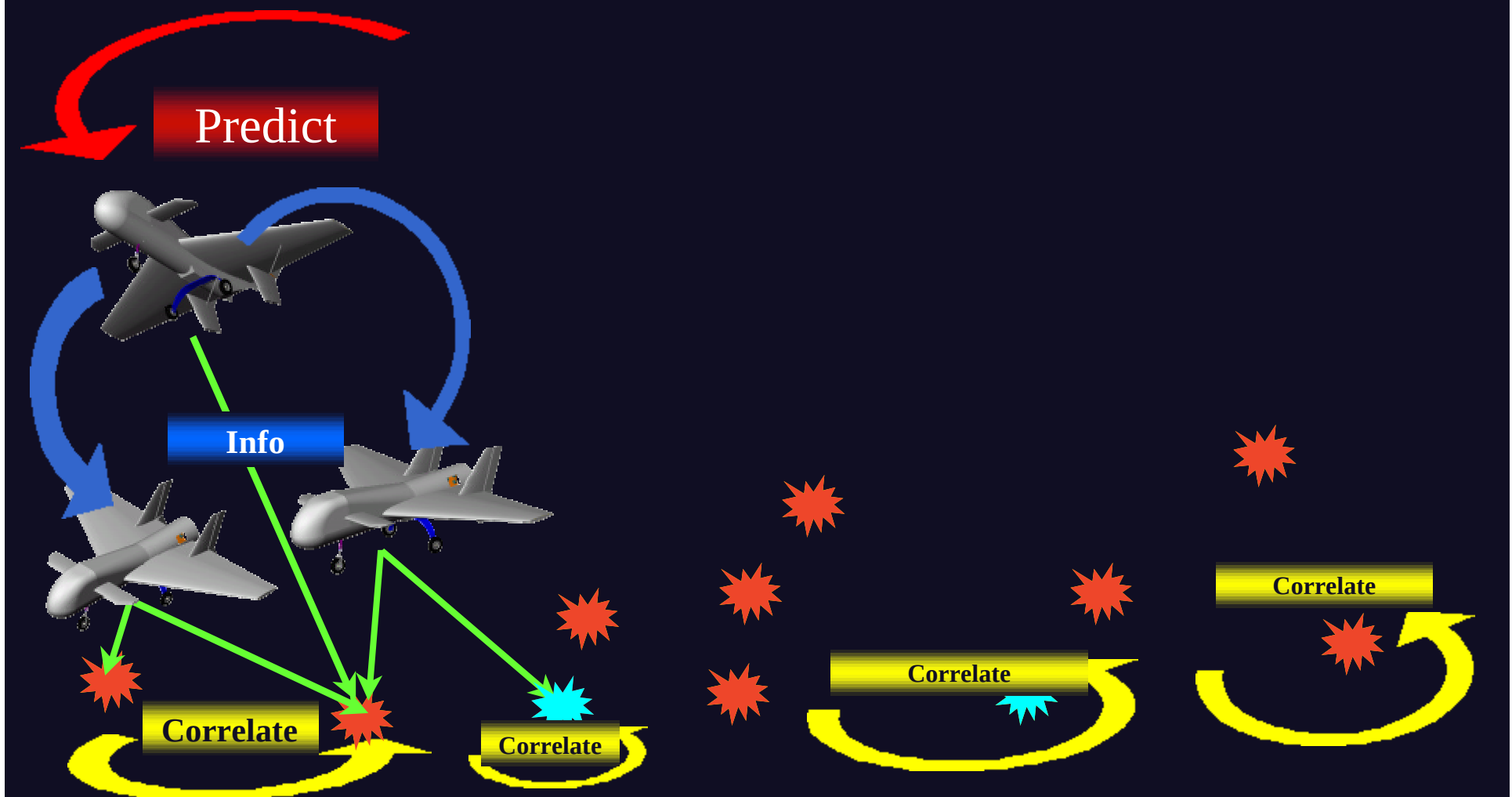
Asequent map data can be employed.

- Multi-Sensor SLAM
 - Reduces Sensor pose error
- Multi-platform SLAM
 - Reduces effect of Platform pose error

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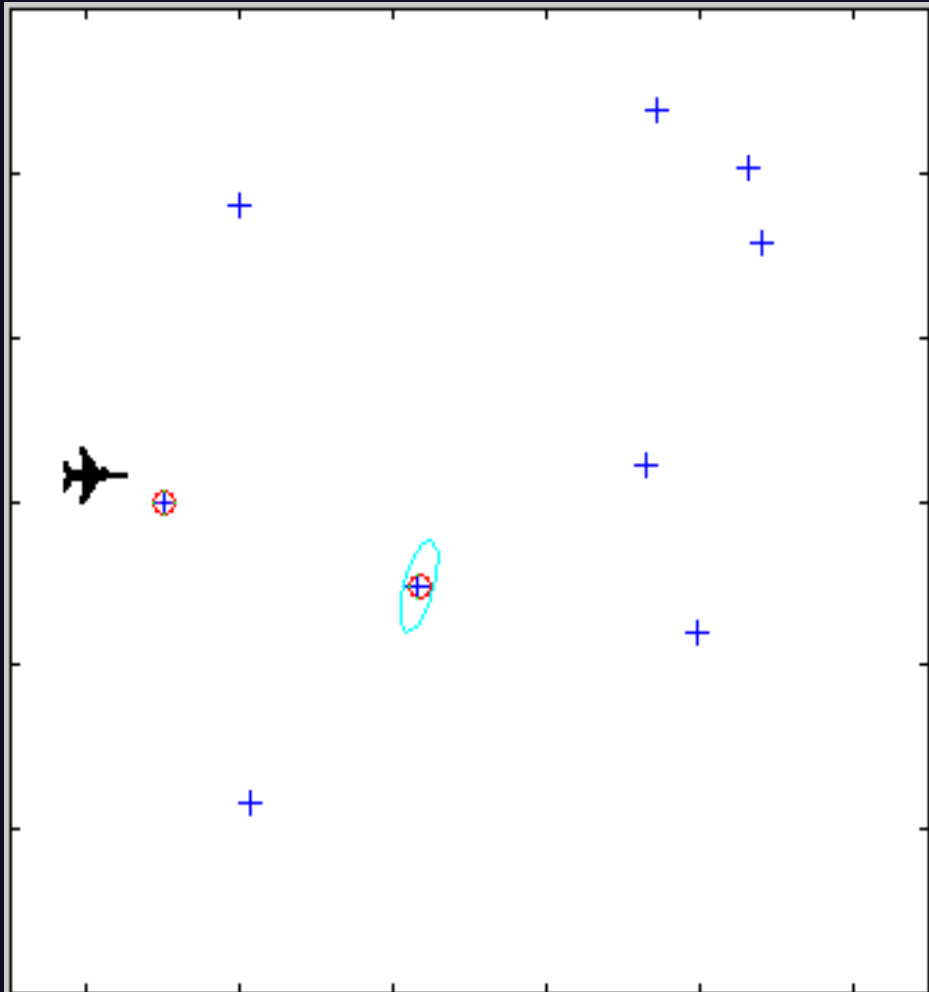




Sequential map-building

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An Example of Platform and Sensor Management



AC1 with 1st sensor payload.

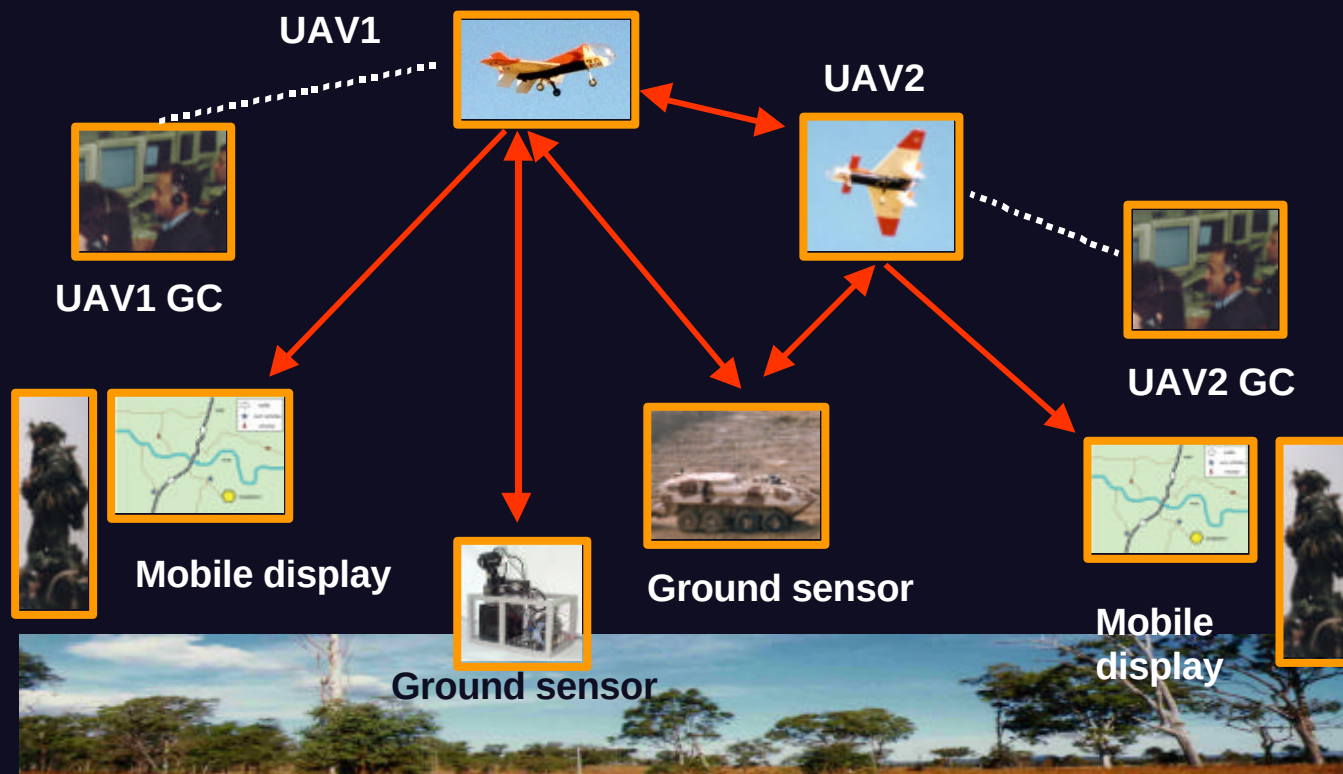
AC2 with 2nd sensor payload.

1. FV1 initiates map building.
2. FV1 propagates map data to FV2.
3. FV2 resumes map building and propagates forward updated map estimates to targets not yet seen by FV2, but which affect FV1.

Future Demonstrations

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- Multiple UAV SLAM
- Mixed Force network SLAM
 - Australian proposed CTD Programme



Summary

- **Mathematical modelling and simulation show**
 - **SLAM provides the means for accurate navigation and target location**
 - **GPS Denied**
 - **No a-priori map data**
 - **DDF provides the means to share map and target data across multiple platforms**
- **Previous land based trials and the latest ANSER flight trials results support the theoretical conclusions**

Additional Benefit

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**Analysis of current UAV Systems performance indicate target
location accuracy will improve by an order of magnitude
through the inclusion of SLAM techniques

even when GPS is available**