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## **ROV-OPERATE: system engineering of an underwater ROV for early verification and automatic synthesis**

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### ► To cite this version:

Rodin Vincent, Vukšić Marko, Kovacevic Tonko, Đukić Predrag, Rogulj Roko, et al.. ROV-OPERATE: system engineering of an underwater ROV for early verification and automatic synthesis. Conference BEING SEA-EU, University of Malta, Jun 2024, Malta, Malta. hal-04641877

**HAL Id: hal-04641877**

**<https://hal.univ-brest.fr/hal-04641877v1>**

Submitted on 9 Jul 2024

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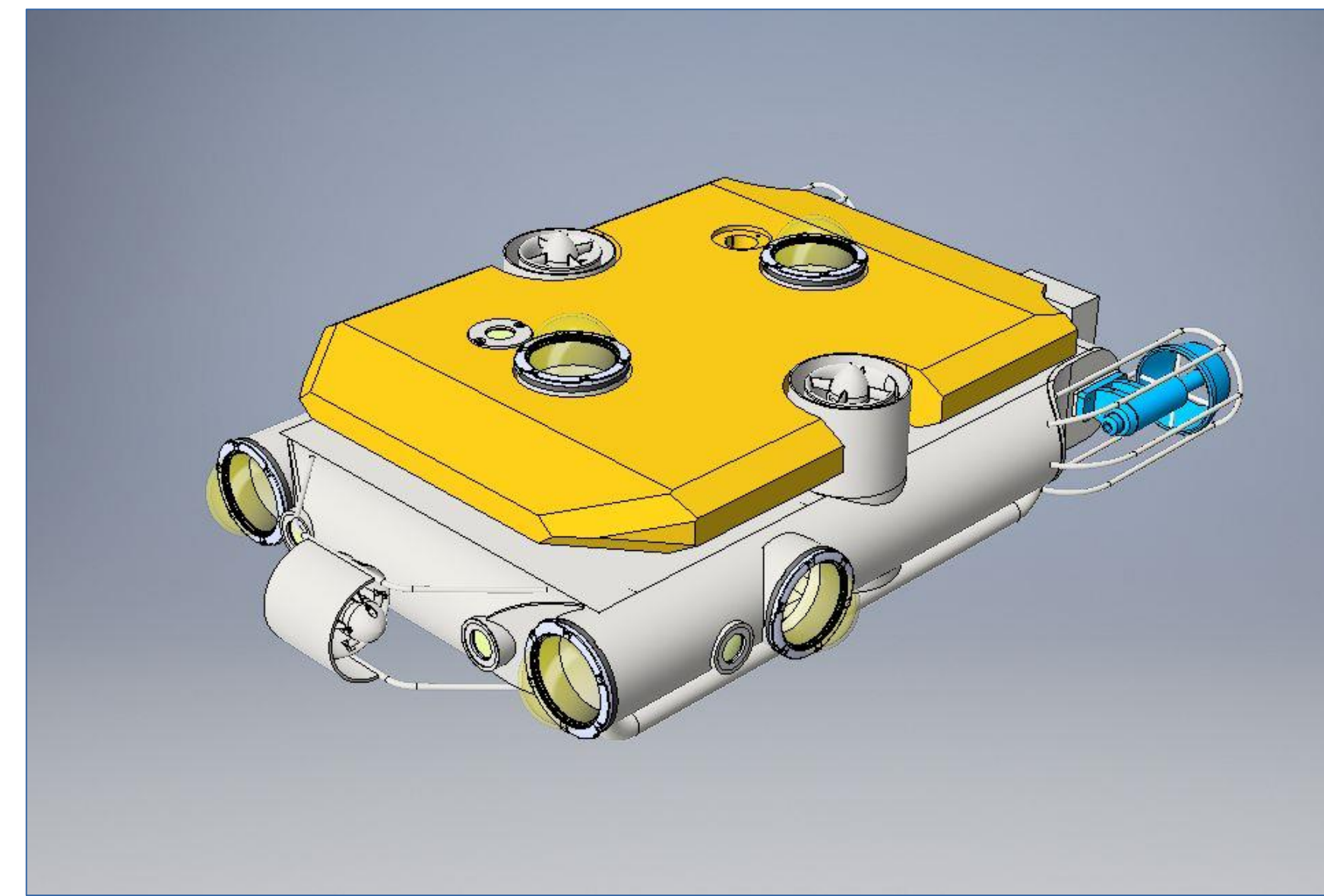
## 1 – Original ROV

- ❑ Very usable, lightweight, maneuverable underwater Remote Operated Vehicle (ROV)
- ❑ Diving down to 150 m depth
- ❑ Inspection of underwater electrical installation
- ❑ Umbilical cable is used to transfer data and electrical power
- ❑ Control by PS2 joystick console
- ❑ Developed by students and professors of the SOSS



## 2 – ROV under development

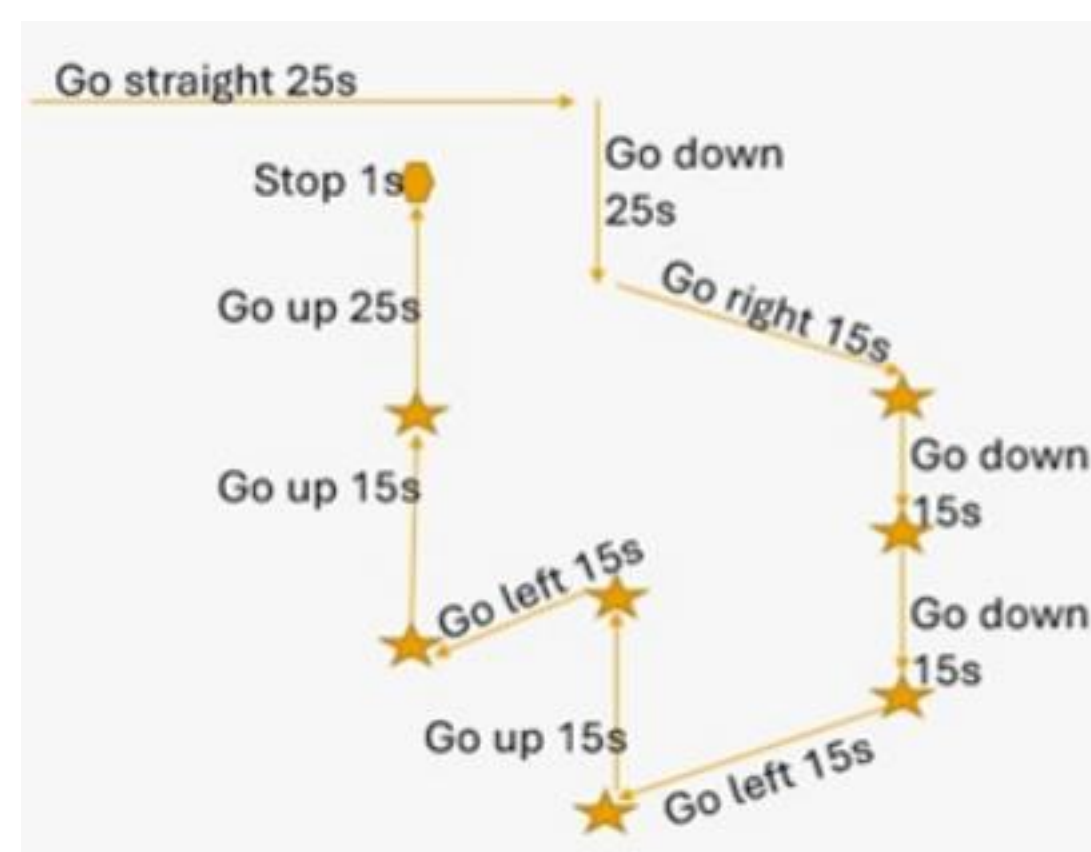
- ❑ Completely autonomous system (without cable)
- ❑ Battery powered - 2 x 625 Wh 36VDC
- ❑ Central control unit - ARK-1551-S6A1
- ❑ Dive control autopilot - Pixhawk 6X
- ❑ Surface control system - computer, joystick, tether interface and screen
- ❑ Advanced communication to surface – Visible Light Communication (VLC) and ultrasound



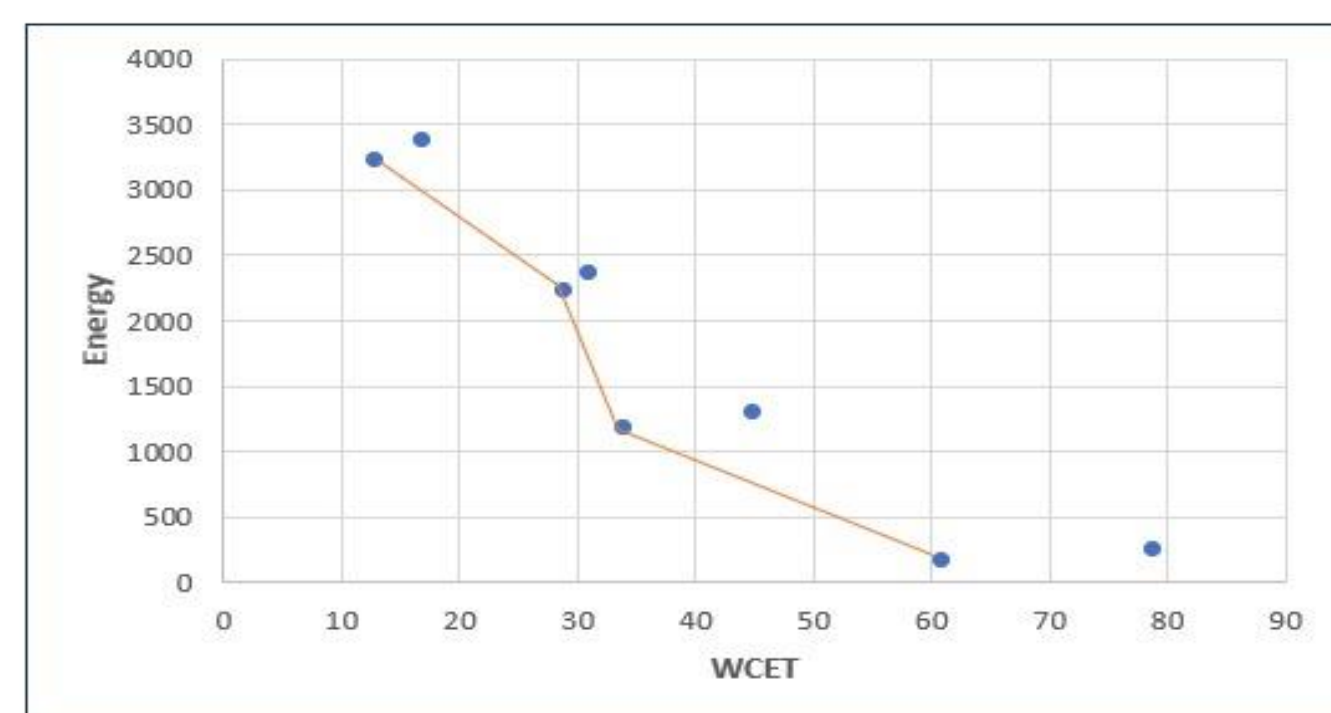
## 3 – Optimizing energy footprint

- ❑ Embed alternative hard/soft components for specific ROV mission achievement

Name	Task Type	Processor Name	Address Space	Capacity	Deadline	Start time	Priority	Blocking TI
GPS	Periodic	cpu1	ad1	2	10	0	1	0
data_encrypt	Periodic	cpu1	ad1	5	10	0	1	0
data_send	Periodic	cpu1	ad1	5	10	0	1	0
down1	Scheduling	cpu1	ad1	25	50	50	1	0



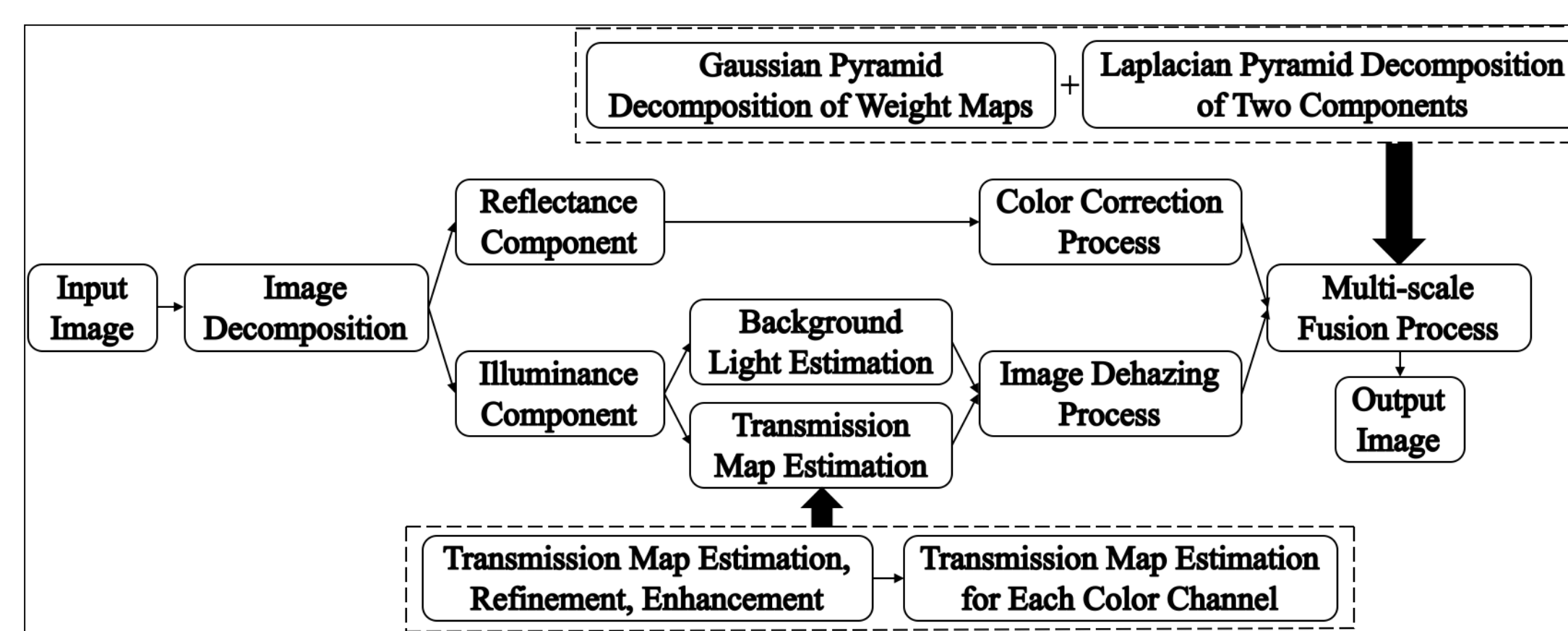
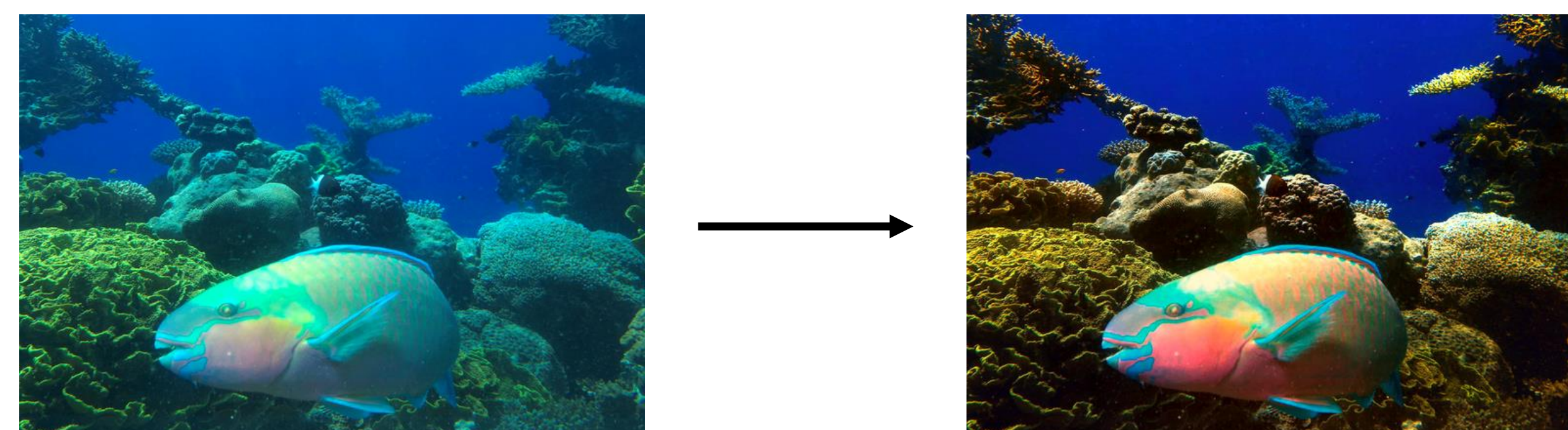
- ❑ Design Space Exploration : find trade-offs between schedulability (WCET) and energy for designs. *example of DSE options: lights, object recognition, DVFS*



- ❑ Use a multi objective optimization tool (PAES) coupled with an architecture simulator (Cheddar) for DSE of tasks scheduling

## 4 – Payload: image processing

- ❑ Underwater images are highly degraded
- ❑ Underwater vehicles need sight for auto positioning
- ❑ Five algorithms for underwater image restoration are compared and the best one is optimized
- ❑ Minimal execution time for real time applications



The general procedure of objects visibility enhancement process

- ❑ Implementation of 360° VR view in real time

The ROV-OPERATE project is funded by the ANR « Investissements d'Avenir: France 2030 » number ANR-19-GURE-0001 in the framework of the ERASMUS + SEA UE consortium

'BEING SEA-EU' 10-12 June 2024



Co-funded by the European Union

