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

Rodin Vincent, Vukšić Marko, Kovacevic Tonko, Đukić Predrag, Rogulj Roko, Šitić Slaven, Džaja Barbara, Turić Hrvoje, Zdroik Jakub, Tran Hai Nam, et al.

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Vincent Rodin<sup>\*,4</sup>, Marko Vukšić<sup>1</sup>, Tonko Kovacevic<sup>1</sup>, Predrag Đukić<sup>1</sup>, Roko Rogulj<sup>1</sup>, Slaven Šitić<sup>1</sup>, Barbara Džaja<sup>2</sup>, Hrvoje Turić<sup>2</sup>, Jakub Zdroik<sup>3</sup>, Hai Nam Tran<sup>4</sup>, Valérie-Anne Nicolas<sup>4</sup>, Alain Plantec<sup>4</sup>, Laurent Lemarchand<sup>4</sup>, Frank Singhoff<sup>4</sup>

1- Department of Professional Studies/University of Split, Croatia, [✉ marko.vuksic@oss.unist.hr](mailto:marko.vuksic@oss.unist.hr)

2- Faculty of Sciences Split/University of Split, Croatia, [✉ bdzaja@pmfst.hr](mailto:bdzaja@pmfst.hr)

3- Department of Physical Oceanography and Climate Research/Univ. of Gdańsk, Poland [✉ jakub.zdroik@ug.edu.pl](mailto:jakub.zdroik@ug.edu.pl)

4- Lab-STICC UMR CNRS 6285/University of Brest, France, [✉ frank.singhoff@univ-brest.fr](mailto:frank.singhoff@univ-brest.fr)

\*: Presenting author: [✉ vincent.rodin@univ-brest.fr](mailto:vincent.rodin@univ-brest.fr)

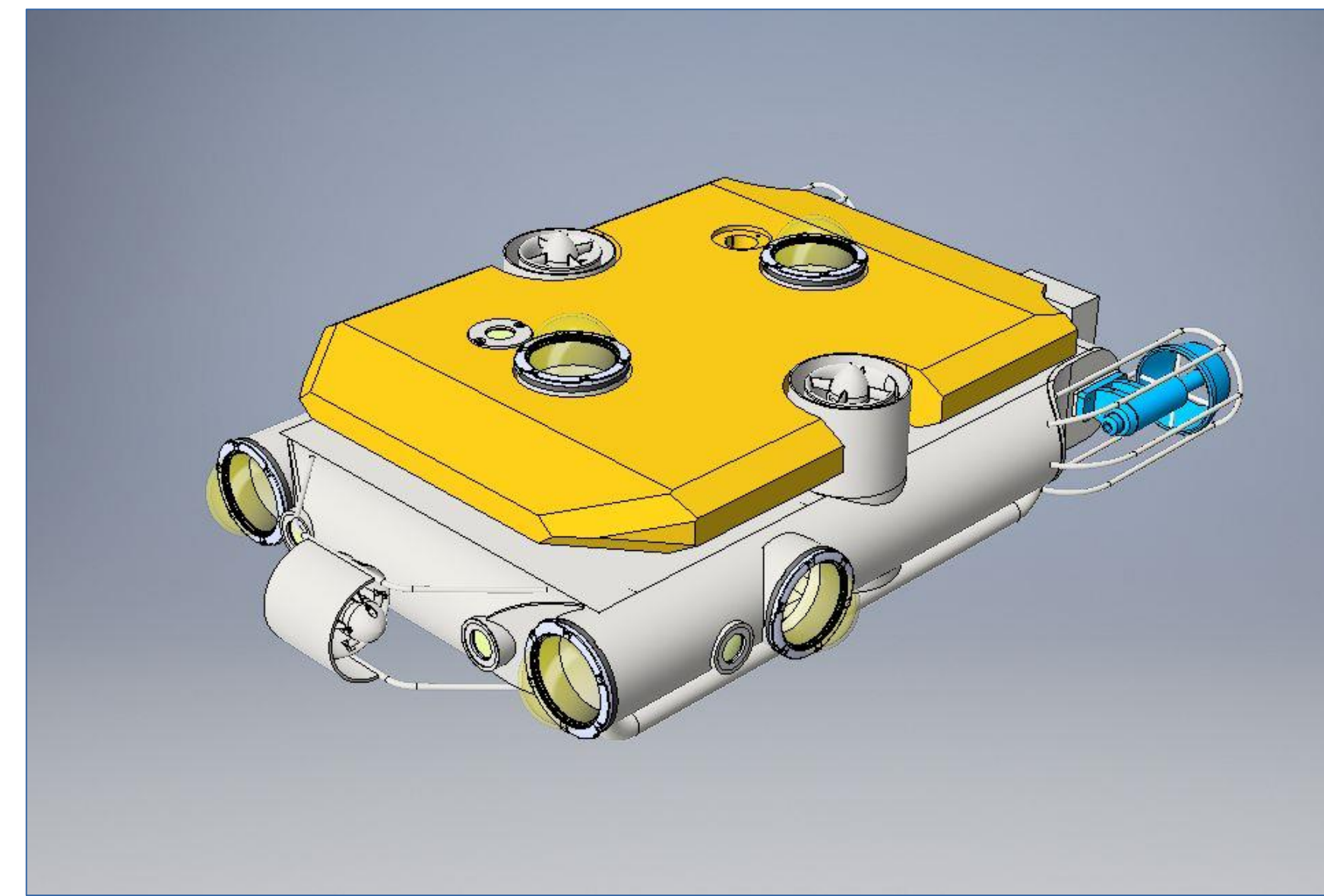
## 1 – Original ROV

- 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

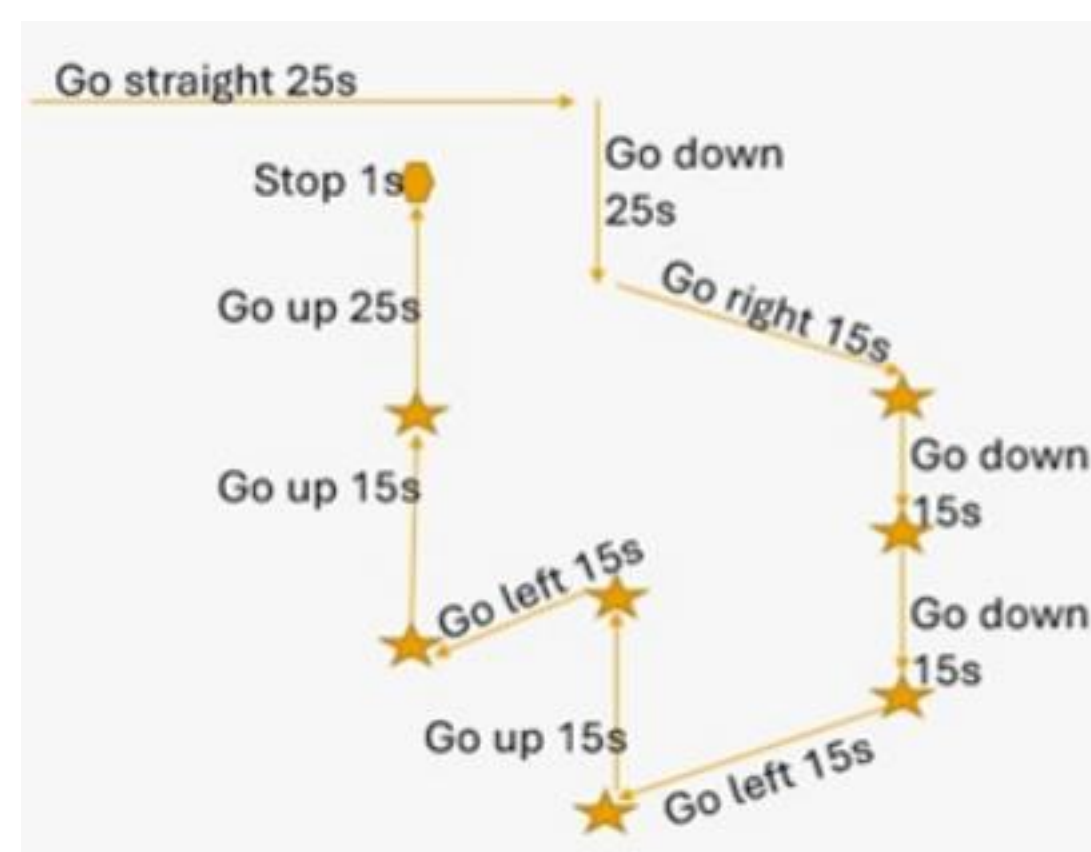
- Completely autonomous system (without cable)
- Battery powered - 2 x 625 Wh 36VDC
- Central control unit - ARK-1551-S6A1
- Dive control autopilot - Pixhawk 6X
- Surface control system - computer, joystick, tether interface and screen
- Advanced communication to surface – Visible Light Communication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



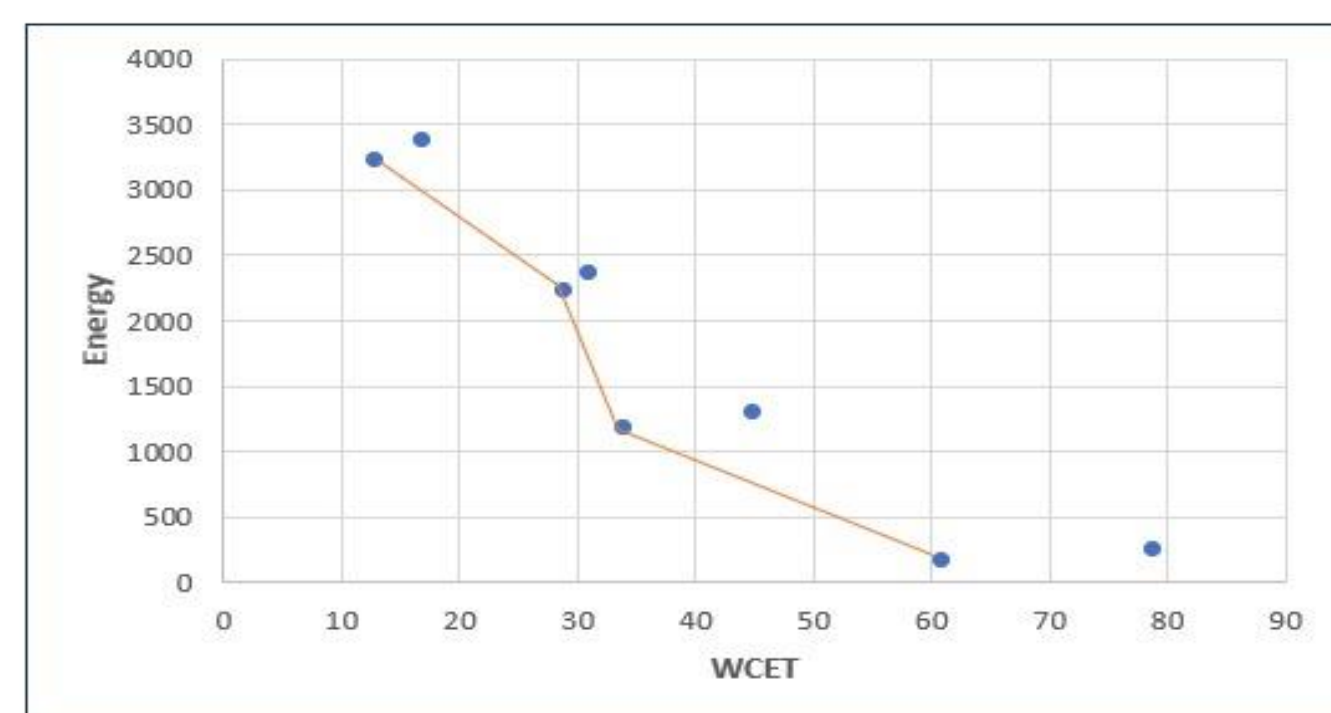
## 3 – Optimizing energy footprint

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

Name	Task Type	Processor Name	Address Space	Capacity	Deadline	Start time	Priority	Blocking Tl
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



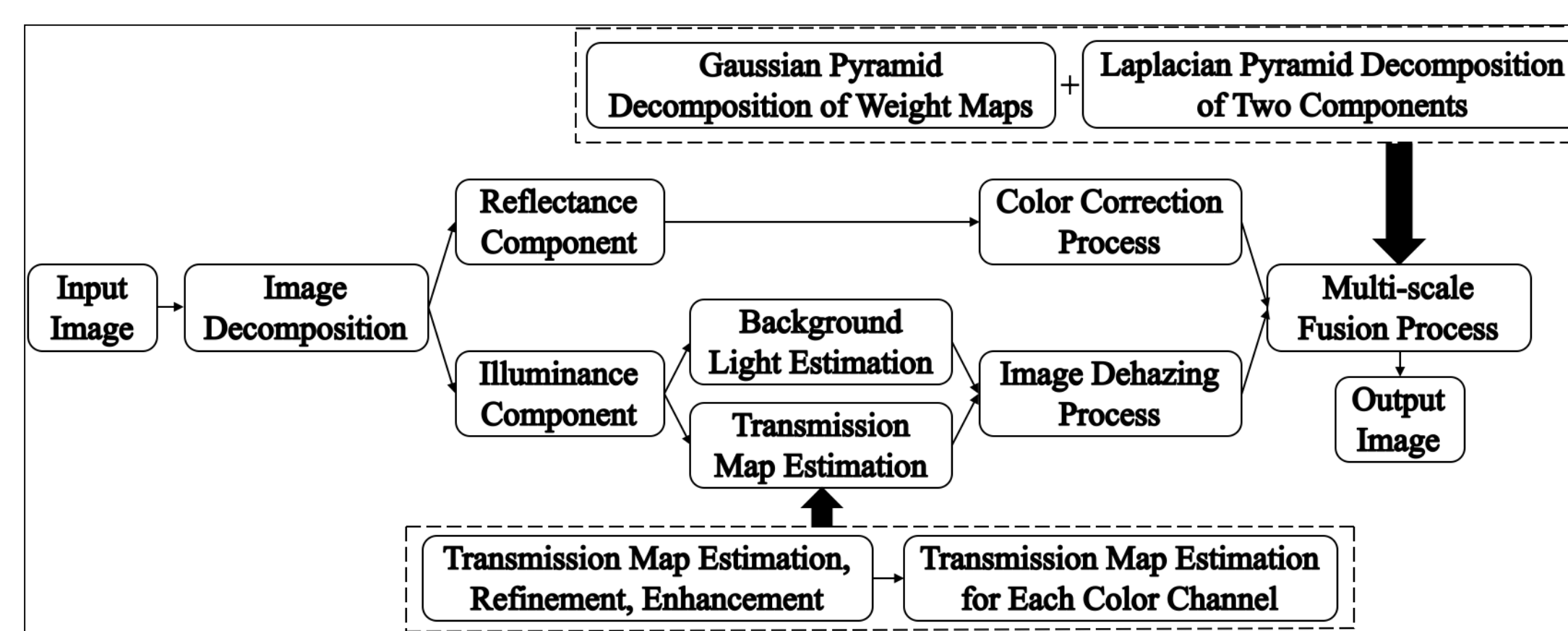
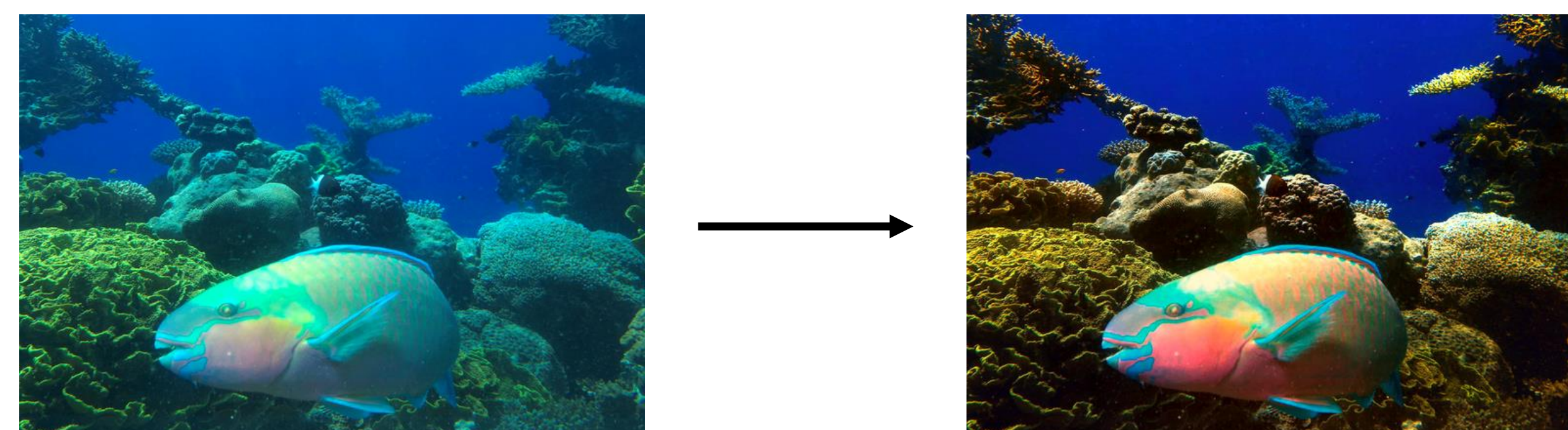
- Design Space Exploration : find trade-offs between schedulability (WCET) and energy for designs. *example of DSE options: lights, object recognition, DVFS*



- 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

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