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# Autonomous Fire-Fighting UAV

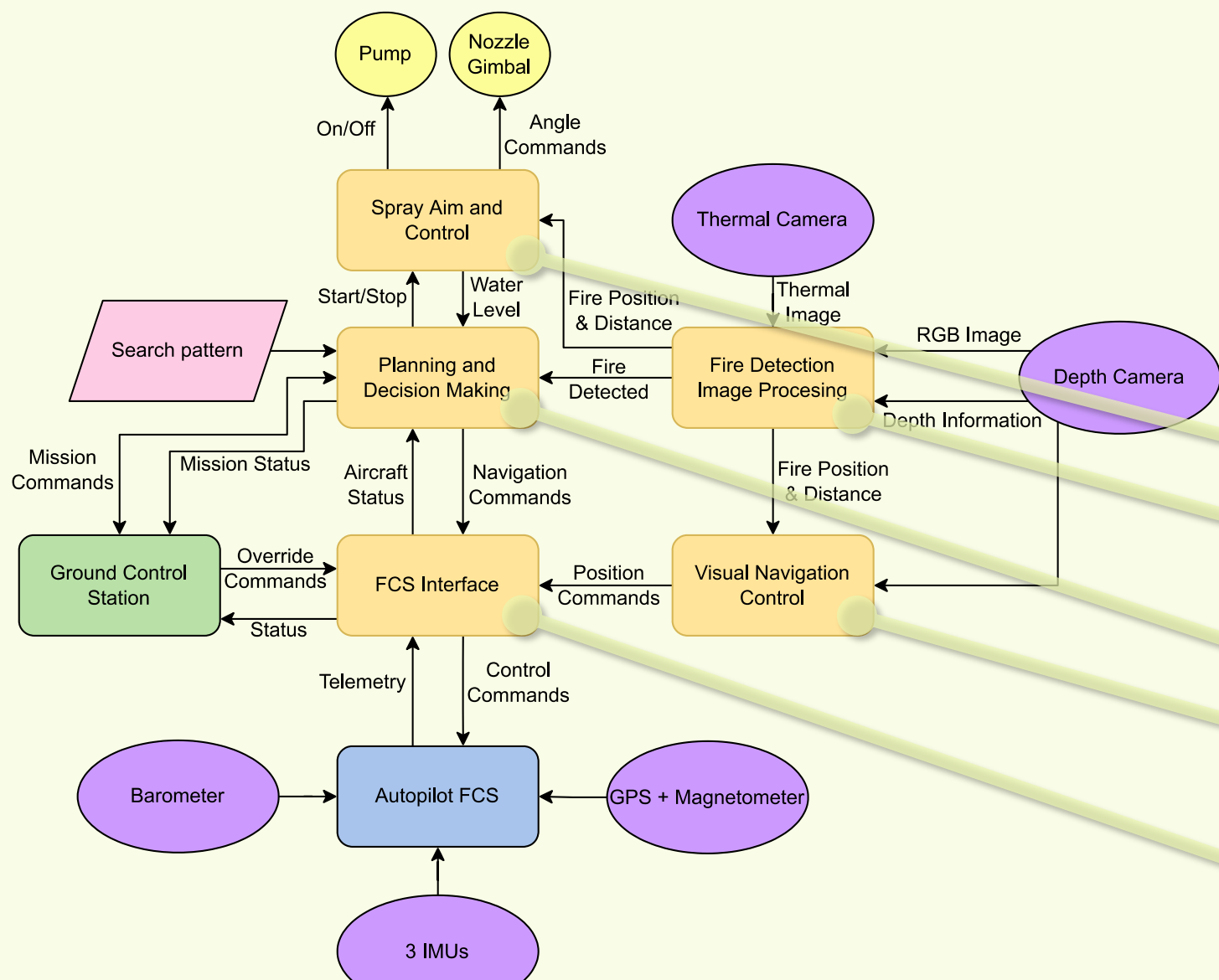
## Description

The primary mission of the autonomous UAV is to search and identify a fire on the wall of a building, fly close to the fire and spray suppressant liquid onto the fire.

## Challenges

- Accurate detection of fire sources using vision-based perception
- Navigation and alignment against centre of fire
- Fire extinguishing from aerial platform

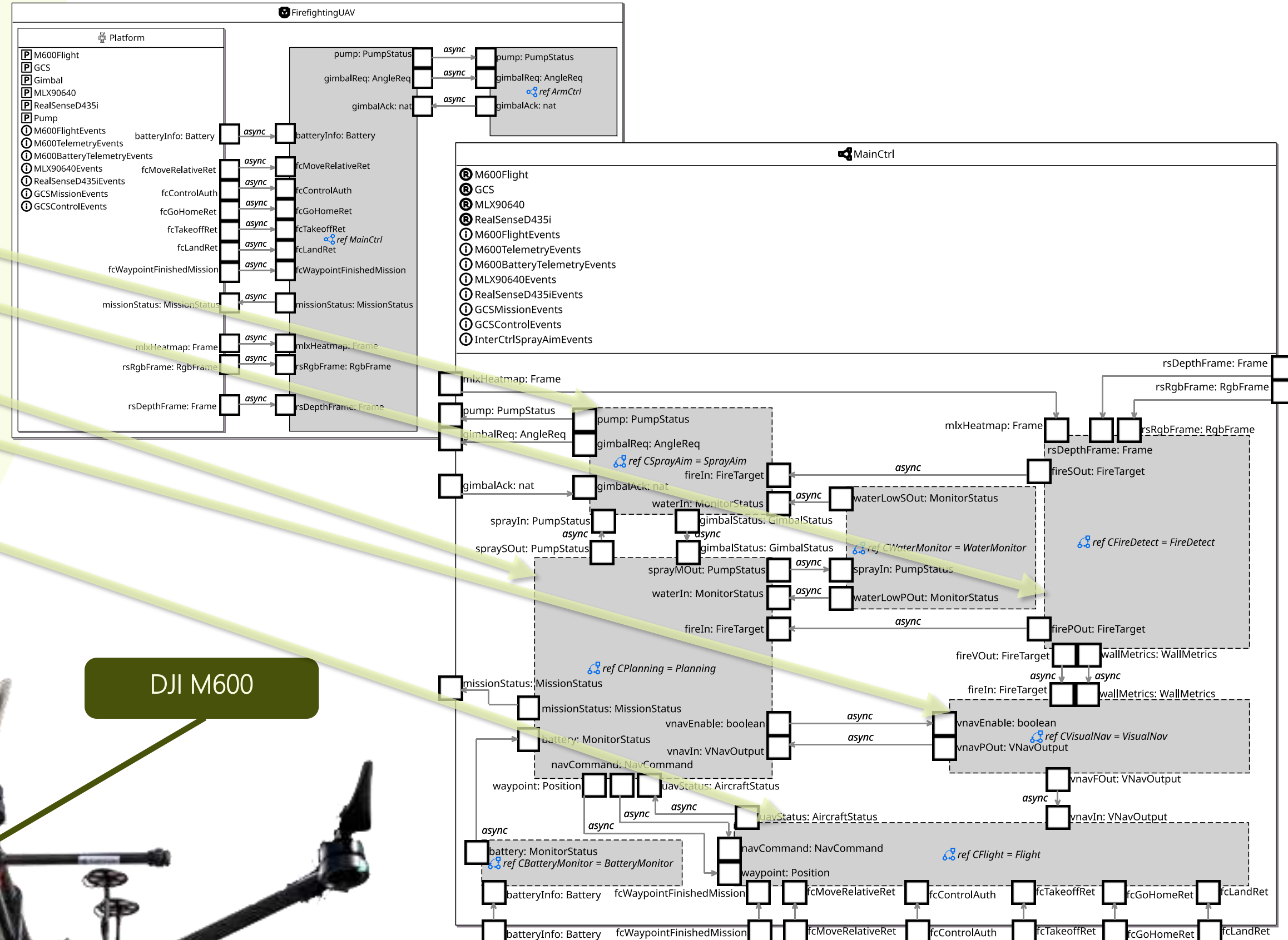
## System Architecture



High level systems diagram with main components and connections.

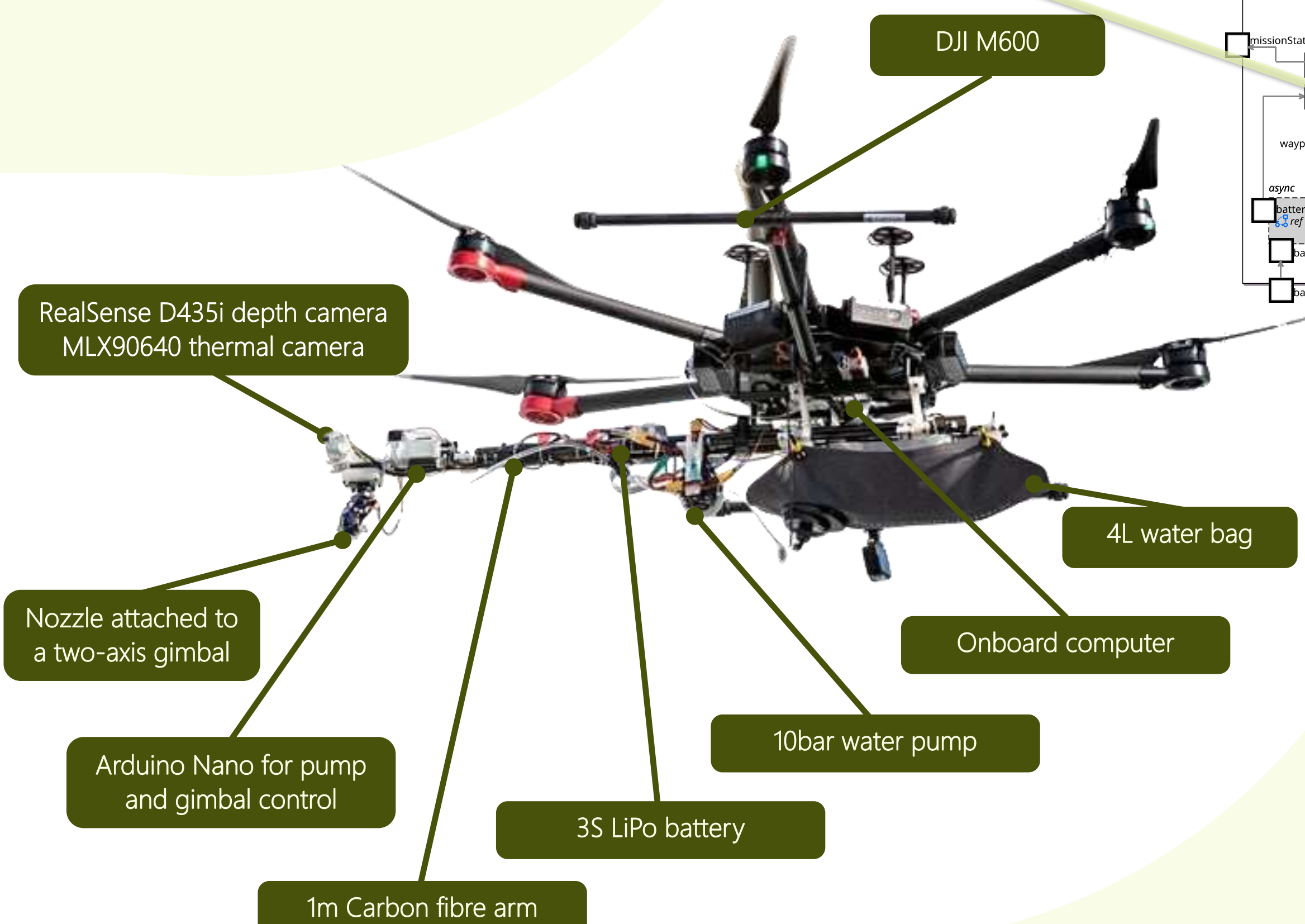
## Software Modelling

- Two RoboChart controllers reflect partition between main computer and Arduino that controls the pump and nozzle gimbal



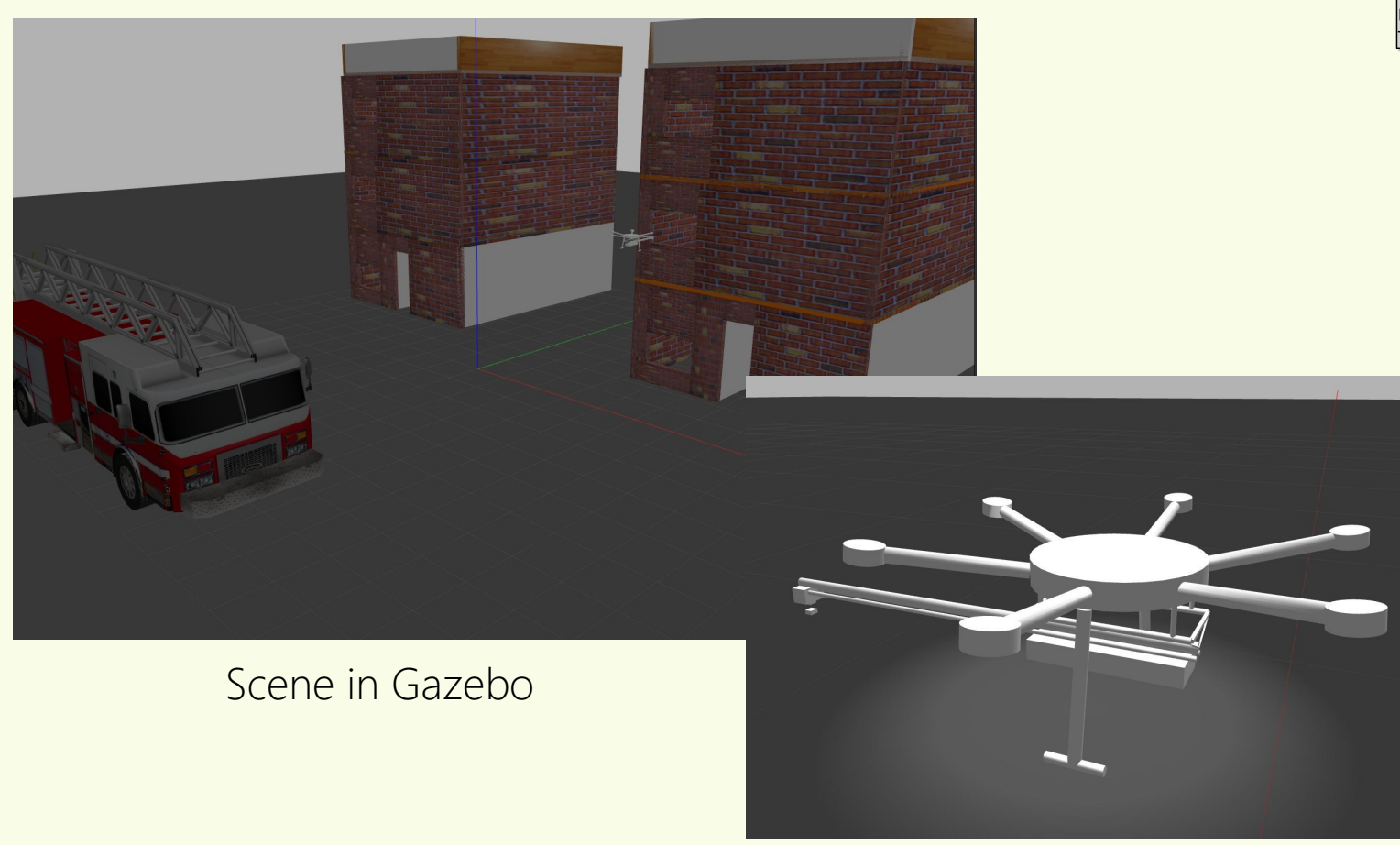
## Physical Modelling

- Modular RoboSim physical model
- Parts reflect decomposition between M600 platform, with GPS, IMU and battery capacity sensors (shown), and custom Payload with cameras, and nozzle gimbal and water pump actuators
- Automatic generation of SDF for simulation with Gazebo



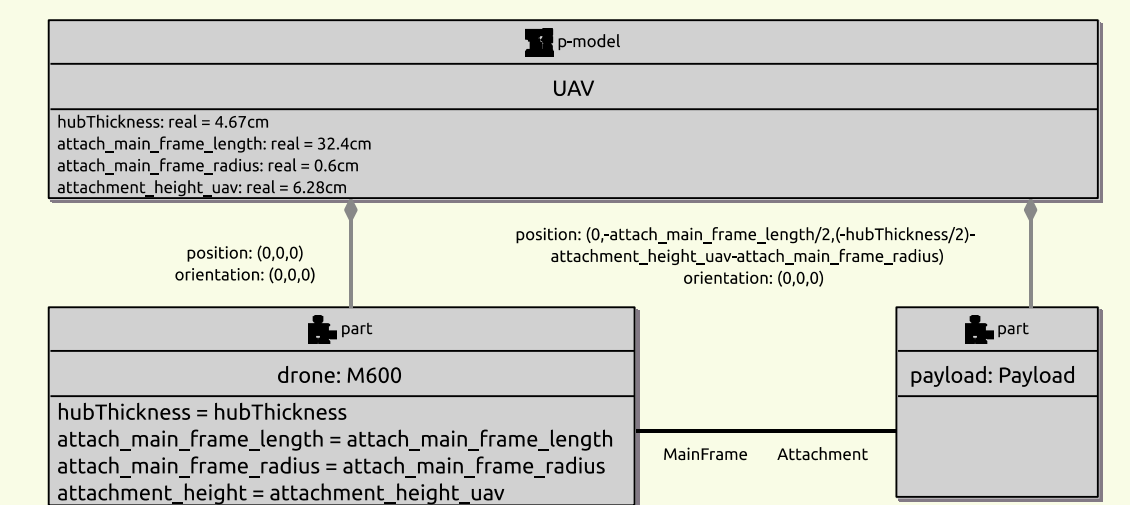
## Simulation

- ROS-based simulation with Gazebo
- Aim to use code generated from RoboSim software model obtained via transformation from RoboChart, ensuring sound behaviour

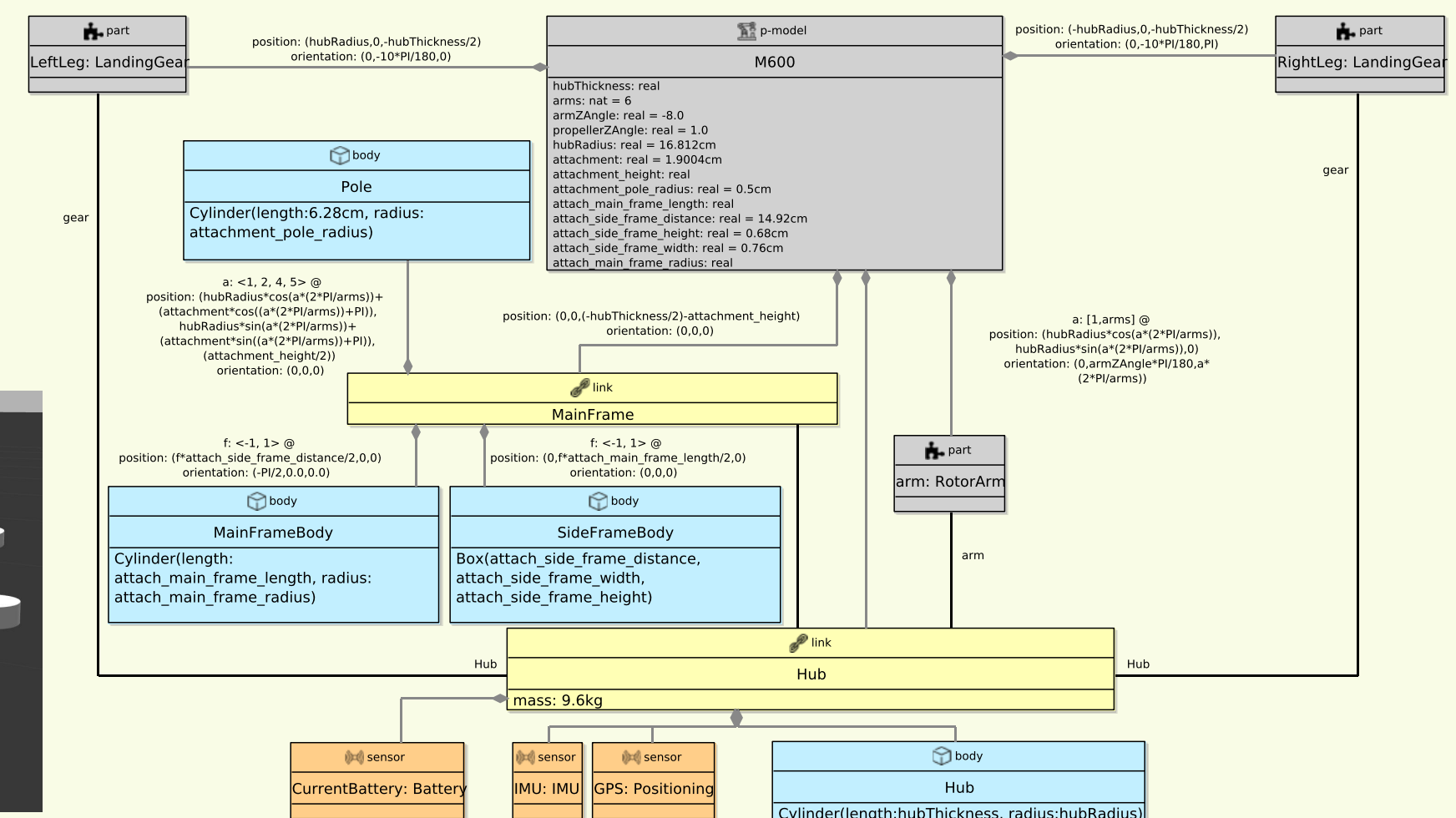


Scene in Gazebo

UAV model rendered in Gazebo after importing generated SDF



RoboSim physical model of the UAV



RoboSim physical model of the DJI M600

## Testing & Verification

- Search-based approach to explore and generate test cases from a digital model
- Conformance testing of the UAV's behaviour against the expected one
- Verification of properties pertaining to the software, platform, and scenario

