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GPS-Guided Real-Time Aerial Surveillance System Design for Monitoring Smart Grid Environment

[1]Dr.P.Gomathi, [2]S.Baskar
[1]Professor/Department of EEE
[2]Assistant Professor/Department of ECE
[1, 2,] N.S.N College of Engineering and Technology
Karur, Tamilnadu, India
Email:p.gomathi2006@gmail.com,connectbaskar@gmail.com

Abstract-Quad copters are the next form of helicopters having more dynamic stability than helicopters. For that reason its miniatures are adapted as Unmanned Aerial cars (UAV) for surveillance, but the trouble is its power source. It may attain vertical flight in a stable manner and be used to watch or gather knowledge in a specific region such as mapping terrains. Technological advances have lowered the fee and broaden the efficiency of the low vigor microcontrollers that allowed most people to advance their possess quadcopter. The purpose of this challenge is to construct, modify, and fortify an existing quadcopter kit to obtain stable flight, accumulate and retailer GPS knowledge, and perform auto-commands, reminiscent of auto-touchdown.

Key phrases: Quad-copter, accelerometer, gyroscope, camera, surveillance procedure, Wi-Fi manage.

I. INTRODUCTION

A quad copter is an aircraft with four main propellers that provides lift. The four motors which drives the propeller are fixed onto a frame that often is made like a cross, made from two beams. The quad copter is almost exclusively used for small drones or radio controlled units today. The quad copter is a popular concept for a drone, because of its properties. The major advantage for the quad copter is its ability to hover, and take off vertically. This makes the quad copter useful for many tasks and allows it to be operated in nearly any environments. The typical design for a quad copter has as stated earlier, no moving parts. The motors and theirs propellers are mounted onto the airframe; this configuration gives the quad copter an interesting dynamic. Since the propellers are fixed to the frame, the only way to induce a lateral motion is to tilt the entire airframe [1]. To tilt the quad copter, the moment about one axis have to alter. To change the moment, one or both motor have to either increase or lower its amount of thrust. If just one of the motors adjusts the thrust, there will be an unbalance in the rotational force about the yaw axis, therefore the motors would have to increase and lower the thrust with the same amount to keep the quad copter still about the yaw axis. This is also the reason for why the motors turning the same direction is mounted opposite to each other, to be able to facility this operation. If the motors had been spinning opposite direction to each other, one could not regulate tilt, without inducing another tilt or yaw moment. Unlike a conventional helicopter, the quadcopter does not have a tail rotor to help controlling the yaw motion. Instead the quadcopter rely on controlling the torque forces from the motors to control the yaw forces. Since the quadcopter is built with four motors where two are spinning clockwise (cw) and the other two spinning counterclockwise (ccw), the torque from the motor [4].

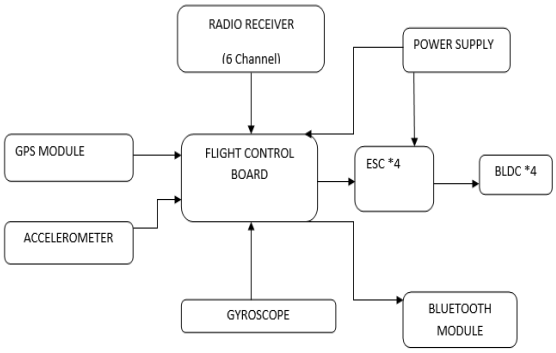

Fig.1.Block Diagram of Quad-copter.

II. LITERATURE REVIEW

A method was once designed to self-reliant land quadcopter using software and substances effortlessly obtainable to scholars and UAV hobbyists. The 3D Robotics quad copter was once chosen after a rigorous selection system for it rugged design, carrying capacity, degree of autonomy supported, open source software, and pre-present group [3]. A control method was once designed utilizing an America radio and open supply software MAV Proxy/MAV Link after the usual program was confirmed inadequate. When purchasing an RC controller to scan and calibrate the digital velocity Controllers (ESCs) of the quadcopter proved to be prohibitively costly, I instead chose to use USB Xbox 360 gaming controller to manipulate the quadcopter manually suggestion the telemetry radio already getting used for in flight commands by way of altering an existing MAV Proxy modules for joystick manage [2]. There was no precedent for calibrating the ESC without a controller but I used to be capable to create an approach to take action as shown in fig 1.

The integration method of a self-sufficient quadcopter platform and the design of Arduino centered novel software structure that allows for the execution of advanced control laws on low-cost and merchandise headquartered frameworks. Right here, quadcopter dynamics are explored through the classical nonlinear equations of motion. Subsequent, quadcopter is designed, developed and assembled utilizing off-the-shelf, low-priced products to carry a digicam payload which is probably utilized for any style of surveillance missions. Approach identification of the quadcopter dynamics is complete by means of the use of sweep information and CIFERr to acquire the dynamic model. The unstable, non-linear quadcopter dynamics are stabilized making use of a standard manage algorithm by means of the radical Arduino centered software architecture. Experimental outcome reveal the validation of the integration and the novel software package strolling on an Arduino board to manipulate self-reliant quadcopter flights. Quadcopters are small rotary crafts that can be used in various environments, the place they're in a position to hold hover capabilities like a conventional helicopter, but are routinely simpler and may obtain greater maneuverability. They use four fixed pitch propellers to manage lift and a combo of propeller torques to manipulate roll, pitch, and yaw [6]. Early designs had poor efficiency as a result of very high pilot workload. Current day manage systems and small sensors have improved the status of the quadcopter as an self-sufficient Unmanned Aerial vehicle (UAV) platform.2

III.METHODOLOGIES

A) PID Controller

The manipulate algorithm that's used to preserve it balance on the autonomous self-balancing two wheel robot was once the PID controller [8]. The proportional, vital, and by-product (PID) controller is well known as a three time period controller. Given that its introduction, greater than sixty years in the past, the PID controller has been the trendy alternative in industrial system control. Due to the simplicity of the controller, it has grown to be the basis for a lot of developed manage algorithms and procedures. The PID controller used to be first presented as a simply mechanical controller [22]. Getting used as a mechanical controller, it noticed its first mechanical implementation on controlling pneumatic programs. After being efficiently being used to manage mechanical programs, it started to be applied in electrical analog circuits. PID implementation in analog circuits has made it possible to manage methods such as house heaters to chemical procedure plants. As microprocessors and microcontrollers have become trendy in manipulate engineering, the PID controller has come to be a fashionable embedded software implementation. This PID controller being implemented in application has outperformed the analog and mechanical types of the controller [5]. The controller can now be programmed onto a single integrated circuit chip.

B) Initialization of The control system

The quadcopter is being initialized prior to the manage loop. The initialization consists of ESC calibration, motor scan and gyro calibration. The initialization is placed in a flat sequence structure and starts with the ESC calibration.

C) ESC instructions

The ESC is calibrated to ensure the maximum and minimal pace instructions are set safely. The calibration procedure starts off via feeding maximum speed command to the ESC before it's powered up [7]. The max pulse will tell the ESC that a calibration will likely be performed. Once the ESC is powered up and beeping with pulses the signal is dropped all the way down to minimum. Then a ramp from minimum to highest is distributed to the ESC. The calibration ends with a minimum velocity command. Throughout the ESC calibration the voltage on each and every ESC is measured. As soon as the ESC is powered up the ESC calibration will routinely. It is also viable to drive a of the motor calibration, and to pass the calibration. Those two choices are usually used in the course of trying out.

D) AVR Programming

The v.5.5 Blackboard has an Atmega168 chip on board which enables customers to tweak and load nonstandard firmware. Set IC Fuses & Flash Flashing the Firmware join the AVRISP Mk2 (or an identical) Programmer to the six pin ISP header on the Flight controller board connect your Programmer's 6 pin socket to the ISP header on the board. Pin 1 on the ISP header is most likely marked with a small triangle. Then connect a 5V DC energy supply to the PCB pins. It's going to open a new window with a connection dialogue asking you to pick your programmer and connection port [9]. With a programmer just like the AVRISP mkII it's easy considering that whilst you opt for that programmer it brings again just one option of USB port. The AVR-ISP500 from Olimex is well-known as a STK500 and has the alternative to auto chosen the port. If it fails to respect the port, you can also have to manually set the port for the programmer on your home windows device settings to COM1 as much as COM4 for AVR Studio to respect it.When you've got chosen your programmer and port, click on connects and you are going to be taken to the AVR programming dialogue. In the AVR programming window go to the "principal" tab and be certain that the chip you are programming (e.G. Atmega168) is chosen in the "gadget and Signature Bytes" drop down menu. Also be certain that the" Programming mode and goal settings are set to ISP. Be certain that the settings for the ISP mode have the ISP frequency set low adequate to talk to the chip [10]. I set my AVRISP500 programmer's frequency to one hundred fifteen.2 kHz. This is really a major atmosphere to get proper. In case you click on on "read Signature" and you get The response "Signature matches chosen gadget" you have

got effectively managed to hook up with your IC. Additionally be certain that the goal board or PCB is powered (that you could determine this by using clicking on the HW Settings tab and checking if the programmer can see any voltage).Now it is time to set the fuses so click on on the "Fuses" tab [12]. AVR Studio is excellent in this respect as it is going to figure out the fuse settings for your exact IC relying upon the determine field options you decide on.

E) Method operate Settings

If you want to store your settings, click "retailer" on the fundamental interface. That you may then supply it a reputation and click "save" to avoid wasting. If you want to open your settings, click "OPEN" on the principal interface. Pick the file and click "OPEN" to open. To adjust the motion of servo to a suitable angle for a better manipulate, click on "Endpoint". Every servo will also be adjusted personally. It is divided into left half of section and right half of phase [13]. Adjusted worth is from zero% to 100%. Which you can enter the numbers straight by means of the keyboard. Click on "good enough" when the adjustment is completed. To restore, click on "Cancel". To alter the path of servo motion, click "Reverse". It continues the transmitter control path comparable to the servo. Click the channel you need to alter. Click "ok" when the adjustment is finished [15]. To regulate single area servo for higher manage of the model, click "Sub Trim". Every servo may also be adjusted personally. Adjusted price is from -120 to 120. You can enter the numbers immediately by means of the keyboard. Click on "good enough" when the adjustment is completed.

IV.HARDWARE IMPLEMENTATION

A) Multiwii Flight Controller

The FLIP MultiWii suitable flight controller is one of the least highly-priced multi rotor flight controllers in the marketplace. Alexandre Dubus began the MultiWii venture decades in the past, in the beginning making use of an Arduino microcontroller linked to a Nintendo Wii gyroscope (already reward within the far flung) to control multirotor plane, which is where the identify "MultiWii" came from.

Fig.2 Multiwii Flight Controller.

It rapidly grew to be increasingly widespread and his application was once adapted to work with a vast kind of sensors [11]. Today the "Multi Wii" challenge is an awfully strong open source application that continues getting better with each revision free up and is compatible with a type of off the shelf flight controllers and sensors.

This record is intended to support you get began using the FLIP (Multi Wii compatible) flight controller as a part of Lynx motion multirotor UAV kits as shown in fig 2.

B) Accelerometer

An accelerometer is a device that measures proper acceleration ("g-force"). Proper acceleration is not the same as coordinate acceleration (rate of change of velocity). For example, an accelerometer at rest on the surface of the earth will measure an acceleration g= 9.81 m/s^2 straight upwards [14]. By contrast, accelerometers in free fall (falling toward the centers of the earth at a rate of about 9.81 m/s^2) will measure zero.

C) Gyroscope

Gyroscopes, or gyros, are devices that measure or maintain rotational motion. MEMS (micro electro mechanical system) gyros are small, inexpensive sensors that measure angular velocity [16]. The units of angular velocity are measured in degrees per second (°/s) or revolutions per second (RPS). Angular velocity is simply a measurement of speed of rotation.

Gyros, similar to the one above, can be used to determine orientation and are found in most autonomous navigation systems. For example, if you want to balance a robot, a gyroscope can be used to measure rotation from the balanced position and send corrections to a motor.

D) ESC – Electronic Speed Controller

The choice of the ESC was done in the preliminary report. The ESC chosen isYGE 60. The ESC suits the motors well with its maximum current of 60 amperes [17]. The ESC has, in contrast to most others commercial products, an option to receive signals up to 100 Hz. High update frequency of the motors are desirable when it comes to the control system. The YGE ESC also offers lower response time due to a lower internal resistance than the normal ESC on the market [19]. The YGE controllers are a good choice for this project. The brushless motors are multi-phased, normally 3 phases, so direct supply of DC power will not turn the motors on. That's where the Electronic Speed Controllers (ESC) comes into play. The ESC generating three high frequency signals with different but controllable phases continually to keep the motor turning. The ESC is also able to source a lot of current as the motors can draw a lot of power.

E) Radio Transmitter and Receiver

The RC Transmitter would probably be the first few things you need to look at. It's a common question for RC beginners how to choose a decent RC transmitter. In this article I will discuss the basics of a RC transmitter and what you should buy. Unlike other parts there isn't much room for you to DIY, so it's common that we would just buy a commercially available transmitter. There are a few things

about functionality you should know before discussing the price, number of channels, modes, frequency and other features as shown in fig 3.

Fig.3 Transmitter and Receiver

F) Video Camera

There are many one-of-a-kind choices for the digital camera. One of the vital first options used to be to mount an IP digicam to the fuselage of the quadcopter which would be equipped to provide an excessive decision image with its possess transmitters shown in fig 4.

Fig.4 Camera module

V.OPERATION

The construction is split in two most important sections, which might be the mechanical and electrical construction. It will have to be famous in the mechanical section, there's produced a design of the quadcopter this design had been on a later stage redesigned as a result of realistic motives which is defined within the same The final design of the quadcopter can also be discovered An normal mechanical drawings for the final design for the quad copter. A quadcopter, also called a quad rotor helicopter or quad rotor, is a multirotor helicopter that's lifted and propelled by using four rotors [18]. Quad copters are categorized as rotorcraft, as opposed to constant-wing plane, in view that their lift is generated by way of a suite of rotors (vertically oriented propellers). Not like most helicopters, quad copters use two units of identical fixed pitched propellers; two clockwise (CW) and two counter-clockwise (CCW). These use variant of RPM to manipulate elevate and torque. Manipulate of car movement is carried out with the aid of altering the rotation expense of one or more rotor discs, thereby altering its torque load and thrust/raise traits.

Early within the historical past of flight, quadcopter (referred to as 'quad rotor') configurations have been seen as possible options to one of the vital continual problems in vertical flight; torque-induced manage problems (as good as efficiency issues originating from the tail rotor, which generates no useful carry) may also be eliminated by way of counter-rotation and the rather brief blades are so much simpler to construct. A number of manned designs appeared in the Twenties and 1930s. These vehicles have been among the first victorious heavier-than-air vertical take-off and touchdown (VTOL) cars. Nevertheless, early prototypes suffered from terrible performance and latter prototypes required an excessive amount of pilot work load, due to negative balance augmentation and constrained manage authority[20]. Extra recently quad copter designs have become well known in unmanned aerial automobile (UAV) research. These automobiles use an electronic control system and electronic sensors to stabilize the plane. With their small size and agile maneuverability, these quad copters can be flown indoors as good as outside. There are a couple of advantages to quad copters over comparably-scaled helicopters. First, quad copters don't require mechanical linkages to vary the rotor blade pitch perspective as they spin. This simplifies the design and preservation of the vehicle. 2nd, using 4 rotors permits each and every person rotor to have a smaller diameter than the identical helicopter rotor, permitting them to own less kinetic vigor during flight[21]. This reduces the harm precipitated will have to the rotors hit something. For small-scale UAVs, this makes the vehicles safer for shut interaction. Some small-scale quad copters have frames that enclose the rotors, enabling flights by means of more difficult environments, with scale down danger of damaging the automobile or its surroundings as shown in fig 5.

Fig.5 Final design of quadcopter

A) Social Relevance

- Used for delivery purpose.
- Security Agencies for observations behind enemy lines.
- For Flood Control to locate stranded people.
- For Real estate videography.
- For Patrolling Oil and Gas pipe lines.
- As Transmission relay station for video links and data links.
- For traffic monitoring on highways.
- For News and Media aerial videography.
- Mining Industry for monitoring the mines.
- Border Patrolling.
- Surveillance in big industrial plants.

VI.CONCLUSION

On this paper, we attempt to overview Unmanned AerialVehicle (UAV) which is a rising technology with a giant talents to revolutionize conflict and to enable new civilian functions. Today UAV play an increasing role in many public missions corresponding to border surveillance, wildlife surveys, military coaching, weather monitoring, and neighborhood regulation enforcement. Accordingly, the Unmanned Aerial vehicle (UAV) required extra exploration. For the period of the evaluate, we also to find some elements that may be further explored someday. We will be able to try to explore deeper on this discipline. A dynamic model of the quadcopter is derived. Deriving this model requires knowledge of rotation matrices which converts forces between special reference techniques. This conversion can also be described in the file. The dynamic mannequin is generated with the aid of summing forces and moments for the quadcopter. The dynamic mannequin is derived to get a figuring out of how the quadcopter behaves. Body constituents were milled in a CNC. From the 3D mannequin the core of gravity used to be adjusted to be localized in the center of the inertial measurement unit. This is not a have to but it makes the attitude estimation less difficult. The quadcopter can keep in touch with a base station over a Wi-Fi radio link using fly sky transceivers. The developed quadcopter is an effective academic platform the place many sensors are implemented.

Our best purpose for this mission used to be to design a quadcopter UAV with reside video surveillance. Very early within the project we learned that quadcopter designs and elements were comfortably to be had and open source. With that expertise we decided to not develop the quadcopter hardware and manipulate software in favor of targeting designing and building the wireless digital camera method and the video analysis. We selected the Aero Quad Cyclone to be a suitable design and determined to use a 35 MHz frequency for the controller. For our video digital camera we determined to make use of a CCTV digital camera because of their small profiles and light-weight weight. The digital camera will then be related to a light-weight 2.4 GHz transmitter to ship the video to the controller display and our pc which helps to monitor the smart grid environment in effective way.

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Authors Profile

Dr.P.Gomathi received the **B.E.** degree in Electrical and Electronics Engineering from Kongu Engineering College, Perundurai, Tamil Nadu, India, in 1998 and **M.E.** in Applied electronics from Kongu Engineering College, Perundurai, and Tamil Nadu India in 2005. She has completed her PhD in Information and communication engineering in 2013 His research interest includes wireless communication Power electronics, smart grid, Sensor Networks, Neural Networks and fuzzy logic, Communication networks

Mr.S.Baksar received the **B.E.** degree in Electronics and Communication engineering from SNS College of technology, Tamil Nadu, India, in 2005 and **M.E.** in VLSI design from SNS College of technology, Tamil Nadu, India, in 2013. His research interest includes wireless communication Sensor Networks, Low power VLSI and Embedded system, Communication networks and IoT.