### Multi Drone Task Allocation

Student: Takudzwa Chakanyuka

Supervisor: Prof Antoine Bagula

Co-Superviser: Mr Mehrdad Ghaziasgar

### Overview

- Background
- Recap
- User Interface Specification
- High Level Design
- Low level Design
- Project Plan

## Background

- Multi drone task allocation (MDTA) consisting of coordinating a team of drones and assigning them tasks
- ▶ This task includes the following subtasks:
  - Target search
  - Task Allocation
  - Drone monitoring

## Recap

### User Requirements and Requirements Analysis

- Target search
  - Coordinates of the locations
- Task allocation
  - Task efficiency
- Drone monitoring
  - Collision avoidance
  - Restricted area avoidance

### User Interface Specification

#### **GUI Elements**:

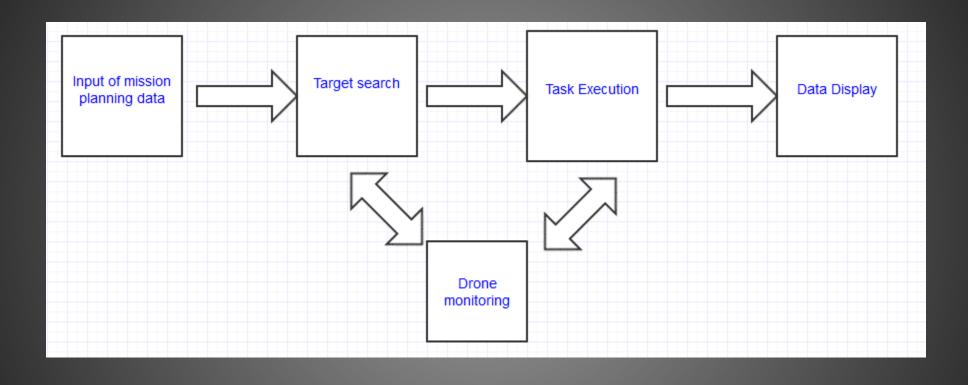
- Welcome screen
- Information and Hints sections
- Search and retrieval interface
- Data entry interface
- Output display section
- Data access section



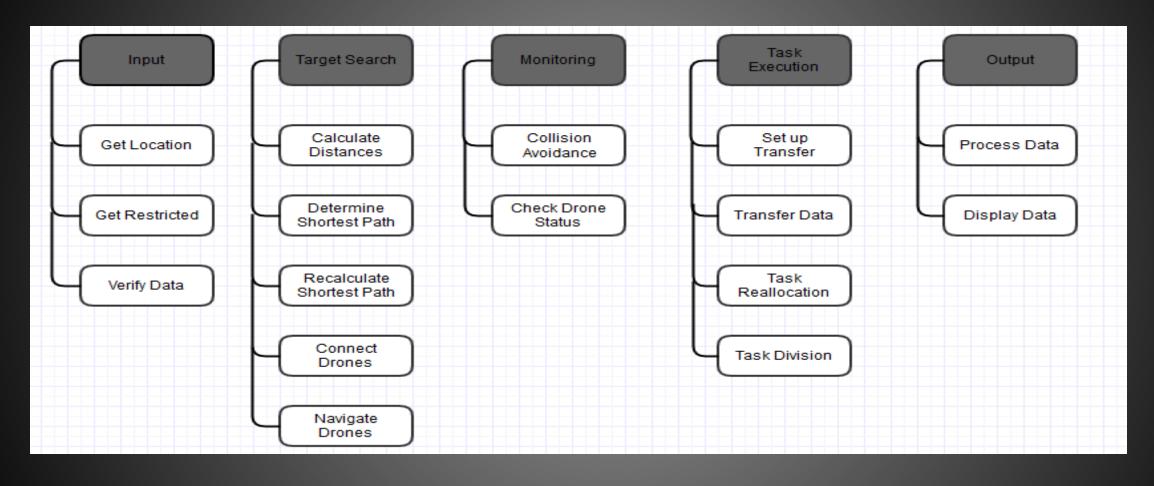
# High level design

- Input of mission planning data
- Target search
- Task execution
- Drone monitoring
- Data display

# Interaction between Subsystems



# Low level Design



## Project Plan

#### Term<sub>1</sub>

- Identify User Requirements, Analyse User Requirements, Literature Survey
- Become Acquainted with OpenCV

#### Term2

- Identify Objects and Classes in the OOD and analyse the Class methods and attributes, Design UI
- Familiarise myself with the Parrot SDK and API

### Term<sub>3</sub>

- Create the Input, Target Search and Task Execution Modules
- Develop the Task Monitoring Application

#### Term<sub>4</sub>

- Test the application against the User Requirements
- Optimise where possible and iron out bugs

### References

- R. Zlot, A. (tony Stentz, M. B. Dias, and S. Thayer, "Multi-robot exploration controlled by a market economy," in *Multi-robot exploration controlled by a market economy*, 2002, pp. 3016–3023.
- [2] X. Ding, A. Rahmani, and M. Egerstedt, "Optimal multi-uav convoy protection," in Robot Communication and Coordination, 2009. ROBOCOMM'09. Second International Conference on. IEEE, 2009, pp. 1–6.
- [3] N. Nigam and I. Kroo, "Persistent surveillance using multiple unmanned air vehicles," in Aerospace Conference, 2008 IEEE. IEEE, 2008, pp. 1–14.
- [4] C. T. Cunningham and R. S. Roberts, "An adaptive path planning algorithm for cooperating unmanned air vehicles," in ICRA, 2001, pp. 3981–3986.
- [5] W. Zhu and S. Choi, "An auction-based approach with closed-loop bid adjustment to dynamic task allocation in robot teams," in *Proceedings of the world congress on engineering*, vol. 2. IAENG., 2011, pp. 1061–1066.
- [6] M. M. Lehata, "Autonomous drone flight," Published as partial fulfilment of the requirements for the degree of Baccalaureus Scientae (Honours) Computer Science University of the Western Cape, 11 2013.