

Table of Contents

Chapter 1. Introduction	1
J.A. GUERRERO	
1.1. Motivation	1
1.2. Historical background	4
1.2.1. Aviation history	4
1.2.2. Evolution of UAVs	7
1.2.3. UAV classification	9
1.3. Flight control	9
1.4. Flight formation control	11
1.4.1. Multiple-input and multiple-output	11
1.4.2. Leader/follower	11
1.4.3. Virtual structure	12
1.4.4. Behavior-based control	12
1.4.5. Passivity-based control	12
1.5. Outline of the book	13
1.6. Bibliography	15
Chapter 2. Theoretical Preliminaries	19
J.A. GUERRERO	
2.1. Passivity	19
2.2. Graph theory	20
2.3. Robustness problems	21
2.3.1. Representation of the parametric uncertainty	23
2.3.2. Families of polynomials	24
2.4. Bibliography	25

Chapter 3. Multiagent Coordination Strategies	27
J.A. GUERRERO, R. LOZANO, M.W. SPONG, N. CHOPRA	
3.1. Introduction	28
3.2. Controllability and observability of interconnections	28
3.2.1. Cyclic topology	29
3.2.2. Chain topology: input and output on agent 1	29
3.2.3. Chain topology: input and output on agent 2	29
3.2.4. Eigenvalues and eigenvectors of the system	30
3.2.5. General case	31
3.2.6. The cyclic topology in the general case	32
3.2.6.1. Observability	33
3.2.6.2. Controllability	33
3.2.7. The chain topology in the general case	34
3.2.7.1. Controllability	34
3.2.7.2. Observability	34
3.2.8. Combinations of chain and cyclic topologies	34
3.2.8.1. Controllability	35
3.2.8.2. Observability	36
3.2.9. Simple configurations that are either non-controllable or non-observable	36
3.2.9.1. Example 1	36
3.2.9.2. Example 2	36
3.2.9.3. Example 3	37
3.2.9.4. Example 4	37
3.2.9.5. Example 5	37
3.3. Formation leader tracking	37
3.3.1. Formation leader tracking in the general case	38
3.3.2. Observer design	39
3.3.3. Simulations	39
3.4. Time-varying trajectory tracking	40
3.5. Linear high-order multiagent consensus	44
3.5.1. Trajectory-tracking control	48
3.6. Conclusion	49
3.7. Bibliography	50
Chapter 4. Robust Control Design of Multiagent Systems with Parametric Uncertainty	51
J.A. GUERRERO, G. ROMERO	
4.1. Introduction	52
4.2. Robust control design	54
4.3. Robust stability analysis	56

4.3.1. Robust strict positive realness	57
4.3.2. Robust absolute stability	60
4.4. Robust stability of time-delay systems	61
4.5. Application to multiagent systems	62
4.5.1. Cyclic topology	62
4.5.2. Chain topology	66
4.5.3. Balanced graph topology	70
4.6. Conclusions	73
4.7. Bibliography	73
Chapter 5. On Adaptive and Robust Controlled Synchronization of Networked Robotic Systems on Strongly Connected Graphs	75
Y.-C. LIU, N. CHOPRA	
5.1. Summary	75
5.2. Introduction	75
5.3. Problem formulation	77
5.4. Adaptive controlled synchronization on strongly connected graphs	79
5.4.1. Delay-free synchronization	79
5.4.2. Synchronization with time delay	81
5.5. Robust controlled synchronization on strongly connected graph	83
5.5.1. Delay-free synchronization	83
5.5.2. Synchronization with time delay	86
5.6. Numerical examples	87
5.6.1. Adaptive tracking algorithm	88
5.6.2. Robust tracking algorithm	90
5.6.3. Disturbances	91
5.7. Conclusions	93
5.8. Appendix	94
5.8.1. Robotic system	94
5.8.2. Graph theory	95
5.9. Bibliography	95
Chapter 6. Modeling and Control of Mini UAV	99
G. FLORES COLUNGA, J.A. GUERRERO, J. ESCAREÑO, R. LOZANO	
6.1. Introduction	99
6.2. General model	101
6.2.1. Translational motion	101
6.2.2. Angular motion	102
6.2.3. Angular rate	103
6.3. Control of a mini tailsitter	103
6.3.1. Linear control strategy	104
6.3.1.1. Roll subsystem	104

6.3.1.2. Pitch subsystem	107
6.3.1.3. Yaw subsystem	108
6.3.2. Robust control considering parametric uncertainty	109
6.3.2.1. Pitch subsystem	109
6.3.2.2. Yaw subsystem	109
6.3.2.3. Roll subsystem	109
6.3.2.4. Time delay case	111
6.3.3. Simulation results	113
6.3.3.1. Linear controller	113
6.3.3.2. Robust controller	115
6.3.4. Experimental results	115
6.4. Quad-tilting rotor convertible MAV	117
6.4.1. Modeling	118
6.4.1.1. Aerodynamics	119
6.4.1.2. FFF mathematical model	122
6.4.2. Transition	123
6.4.3. Control strategy for hover flight mode	125
6.4.4. Control strategy for forward flight mode	127
6.4.5. Simulation results	129
6.4.5.1. HF mode	129
6.4.5.2. FFF mode	131
6.5. Concluding remarks	131
6.6. Bibliography	132
Chapter 7. Flight Formation Control Strategies for Mini UAVs	135
J.A. GUERRERO	
7.1. Introduction	135
7.2. Formation geometry	137
7.2.1. Triangular formation	137
7.2.2. Line formation	138
7.3. Communication network	138
7.4. Dynamic model	139
7.5. Formation flying control based on coordination	142
7.5.1. Formation control	147
7.6. Formation flying control based on nested saturations	148
7.6.1. Formation control	152
7.7. Trajectory-tracking control	153
7.7.1. Time-varying reference tracking	155
7.7.1.1. Chain topology	156
7.7.1.2. Cyclic topology	157
7.8. Simulation results	158
7.8.1. High-order consensus-based formation	158
7.8.2. Nested saturations based formation	159

7.8.3. Time-varying tracking	159
7.9. Conclusions	162
7.10. Bibliography	162
Chapter 8. Formation Based on Potential Functions	165
L. GARCÍA, A. DZUL	
8.1. Introduction	165
8.2. Dynamical model	166
8.3. Formation control	167
8.3.1. Interactive potential energy and force	167
8.3.2. Collision avoidance	169
8.3.3. Obstacle avoidance	169
8.3.4. Total structural force	170
8.4. Position control	170
8.4.1. Altitude and yaw control	171
8.4.2. Nested saturation control	171
8.4.2.1. Change of variables for the nested saturation	172
8.4.2.2. Nested saturation formation control	174
8.4.3. Stability analysis	175
8.4.4. Stability analysis for the interconnected system	176
8.4.5. Bounded force	181
8.4.6. Repulsive distance	182
8.5. Simulation results	183
8.5.1. Obstacle avoidance	185
8.5.2. Multiple formations	187
8.6. Conclusions	189
8.7. Bibliography	189
Chapter 9. Quadrotor Vision-Based Control	191
J.E. GOMEZ-BALDERAS, J.A. GUERRERO, S. SALAZAR, R. LOZANO, P. CASTILLO	
9.1. Introduction	191
9.2. Quadrotor dynamic model and control	194
9.2.1. Dynamic model	194
9.2.2. Nonlinear control	194
9.2.3. Trajectory-tracking control	195
9.3. Computer vision preliminaries	197
9.3.1. Camera model	197
9.3.2. Projective distortion removal	199
9.3.3. Affine distortion removal	200
9.4. Tracking of a visual target	201
9.4.1. Edge-detection algorithm	202
9.4.2. Polygons properties	202

x Flight Formation Control

9.4.3. Square-detection algorithm	204
9.4.4. Image rectification	204
9.4.5. Solving the 3D localization problem	205
9.4.6. OF measurement	207
9.5. Tracking of a visual line	209
9.5.1. Vanishing point detection	209
9.6. Embedded architecture	214
9.7. Experimental results	214
9.7.1. Visual target position stabilization	214
9.7.2. Tracking of a visual line with no marks	218
9.8. Conclusions	221
9.9. Bibliography	221

Chapter 10. Toward Vision-Based Coordination

of Quadrotor Platoons	225
L.R. GARCÍA CARRILLO, J.A. GUERRERO, R. LOZANO	

10.1. Introduction	225
10.2. Problem statement	227
10.2.1. Description of the process	227
10.2.2. Objective of our approach	228
10.3. Dynamic model and control of a quadrotor	228
10.3.1. Dynamic model	228
10.3.2. Vehicle stabilization	228
10.4. Vision-based position estimation	229
10.4.1. Visual system setup	230
10.4.2. Computing the 3D position	231
10.4.3. Translational velocities	233
10.4.4. Prediction of the landing pad position	234
10.5. Coordination position control of two quadrotors	235
10.6. Architecture of the experimental platforms	237
10.6.1. Quadrotor system	237
10.6.2. Ground station	238
10.6.3. Monocular imaging system implementation	239
10.7. Experimental results	240
10.8. Conclusions and future work	242
10.9. Bibliography	243

Chapter 11. Optimal Guidance for Rotorcraft Platoon Formation

Flying in Wind Fields	247
J.A. GUERRERO, Y. BESTAOUI, R. LOZANO	

11.1. Introduction	247
11.2. Preliminaries	250
11.2.1. Dynamic model	250

11.2.2. Vehicle control	250
11.3. Path planning	251
11.3.1. Center of mass of the platoon	251
11.3.2. Zermelo navigation problem: case 2D	251
11.3.2.1. Navigation equation	252
11.3.2.2. One particular solution	253
11.3.3. Zermelo navigation problem: case 3D	254
11.3.3.1. Constant wind	257
11.3.3.2. Linear variation of wind velocity	257
11.4. Quadrotor formation control scheme	258
11.5. Quadrotor trajectory-tracking control	258
11.6. Simulation results	259
11.6.1. Reference given to leader vehicle	260
11.6.2. Reference given to all vehicles	262
11.7. Conclusions and future work	264
11.8. Bibliography	264
Chapter 12. Impact of Wireless Medium Access Protocol on the Quadrotor Formation Control	267
J.A. GUERRERO, Y. CHALLAL, P. CASTILLO	
12.1. Introduction	267
12.2. Multi quadrotor consensus	269
12.2.1. Quadrotor dynamic model and control	269
12.2.2. From individual to collective behavior	270
12.3. Multiagent consensus over wireless networks	272
12.3.1. CSMA/CA	272
12.3.2. TDMA	273
12.3.3. Network analysis	273
12.4. Quadrotor consensus over wireless networks	275
12.5. Simulation results	278
12.6. Conclusions and future work	282
12.7. Bibliography	282
Chapter 13. MAC Protocol for Wireless Communications	285
A. MENDEZ, M. PANDURO, O. ELIZARRARAS, D. COVARRUBIAS	
13.1. Introduction	285
13.2. Protocols of medium access control	287
13.2.1. Slotted ALOHA	287
13.2.1.1. Modeling of S-ALOHA	287
13.2.2. Carrier sense multiple access	290
13.2.2.1. Modeling of CSMA	290
13.2.3. Inhibit sense multiple access	292
13.2.3.1. Modeling of ISMA	292

13.2.4. Results of performance evaluation	294
13.3. Proposed MAC protocol	296
13.4. Experimental setup and results	299
13.5. Conclusions	300
13.6. Acknowledgments	301
13.7. Bibliography	301
Chapter 14. Optimization of a Scannable Pattern for Bidimensional Antenna Arrays to Provide Maximum Performance	305
A. REYNA, M.A. PANDURO, A. MENDEZ	
14.1. Introduction	305
14.2. Design of planar antenna arrays	306
14.2.1. Theoretical model	306
14.2.2. Objective function used to optimize planar arrays	307
14.2.3. Results obtained for the design of planar arrays	308
14.3. Design of concentric ring arrays	314
14.3.1. Theoretical model	314
14.3.2. Results obtained for the design of concentric ring arrays	316
14.4. Discussions and open problems	319
14.5. Conclusions	320
14.6. Acknowledgments	320
14.7. Bibliography	320
List of Authors	323
Index	325