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Abstract. This paper presents the trajectory tracking and the path planning algorithm based on an adaptive control law to operate a complex-shaped low speed autonomous underwater vehicle (AUV) in a challenging environment of non-linearity, time variance and unpredictable external disturbances. Firstly, computational fluid dynamic (CFD) simulations are used to compute the added mass matrix and the damping matrix.

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A 3-2-1 rotation from F. through yaw (?), pitch (?), and roll (?) angles: $R_{bi} = R_1(?)R_2(?)R_3(?)$ Reference Frames for Ship D&C (2) Illustration (from T. Fossen's Guidance and Control of Ocean Vehicles) shows relationship between intermediate axis systems and roll, pitch, and yaw, angles.

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Thor I. Fossen

This paper aims to review fuzzy-logic-based guidance and control in an important branch of robots—marine robotic vehicles. First, guidance and motion forms including the maneuvering, path following, trajectory tracking, and position stabilization are described.

Survey on Fuzzy-Logic-Based Guidance and Control of Marine ...

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Guidance And Control Of Ocean Vehicles

This book is one-of-a-kind, as far as I have been able to determine, in that it is the only book that deals specifically with the guidance and control of marine vehicles. The book deals mainly with the modeling and control of unmanned untethered underwater vehicles (remotely operated vehicles and autonomous underwater vehicles) and high speed ...

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