



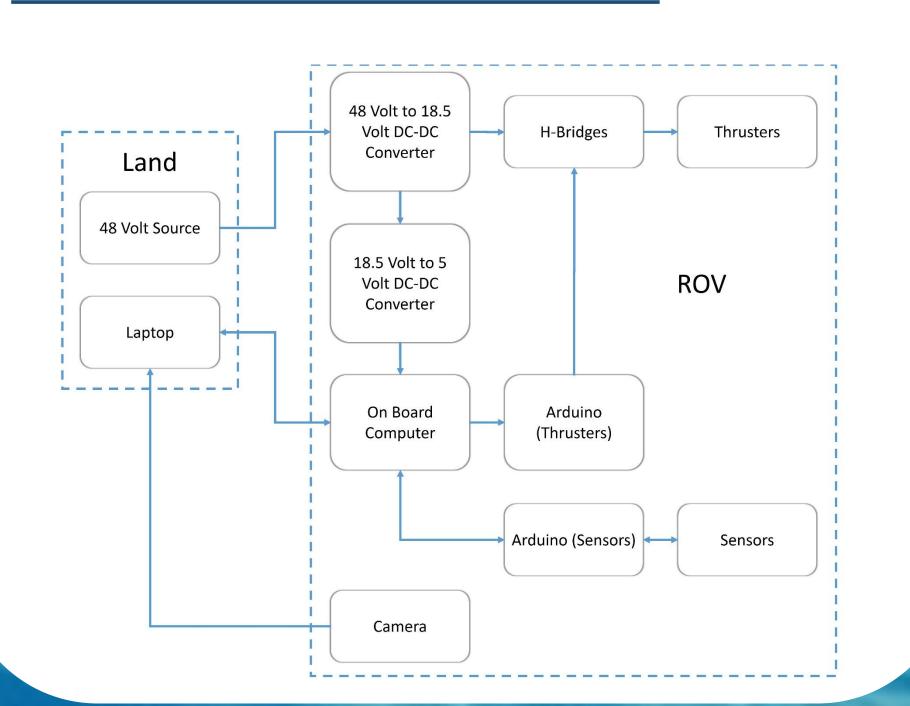


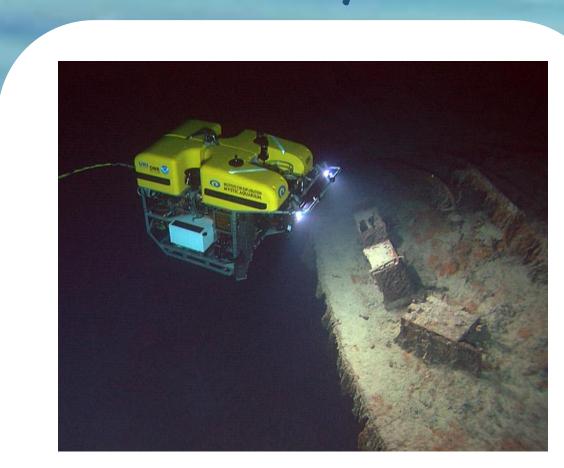
Underwater Remotely Operated Vehicle

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Electronics Schematic





Application of ROV investigating Shipwreck

Project Goals & Applications

- 2014 MATE ROV Competition
 - Shipwreck exploration mission
 - 3 categories: Identification, Science, and Conservation
 - Gain information to identify shipwreck
 - Take scientific samples and return to surface
 - Remove debris/waste

• Test Platform for PhD Research

- Provide ROV for optic sensing research
- For use with leader-follower technology in unmanned underwater vehicles (UUVs)
- Applications with ocean mapping
- 2nd ROV to be built summer 2014 to test optic sensing between vehicles

Control Scheme

- Arduino Mega (2)
- Beagleboard XM
- IMU (inertial measurement unit)
- H-bridge (6)
- PS3 Controller
- Microsoft LifeCam
- Combination temperature/humidity (CTD) sensors
- Pressure sensors

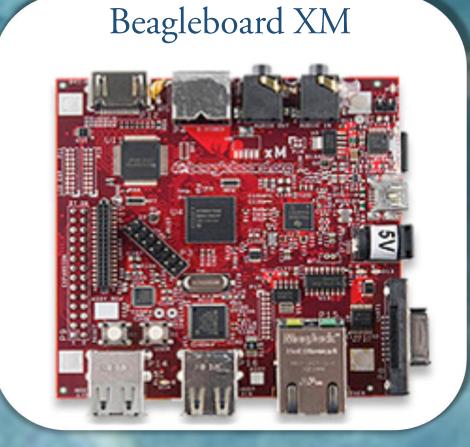
Chassis Design

- Minimize size in accordance with mission tasks
- Maintain slight positive buoyancy
- Symmetry to eliminate roll
- Waterproof housing of electronics and camera
- Safe mounting of tether on rear of ROV
- Space for PhD research equipment



GUI & Coding

- Communication with onboard computer (Beagleboard)
- Control of all 6 thrusters in both directions with ps3 controller
- Readouts from temperature and humidity sensors through Arduino
- Display of vehicle's orientation based on data from IMU
- Video feed through USB





Propulsion Design

- Pitch and Yaw control
- 6 thrusters for 3 translational degrees of freedom
- Reversible thrusters for ease of control
- Position around center of mass



UNH Ocean Engineering Dept., UNH Mechanical Engineering Dept., UNH Electrical & Computer Engineering Dept., Tara Hicks-Johnson, Jenn Bedsole, Sheri Millette, Tracey Harvey, Paul Lavoie, CEPS Dean's Office, Parents Association, Kevin Maurer, Jeff Maggio, Max Cinq-Mars, Chris Brown, The Boudreau Family













