Motion automation of remotely operated underwater vehicle for mine countermeasures

© S.A. Yegorov

Bauman Moscow State Technical University, Moscow, 105005, Russia

The paper presents a new approach to motion control system designing of a remotely operated underwater vehicle for mine countermeasures. The approach enables to automate mine countermeasures operations and it is based on separating different control modes.

Keywords: remotely operated underwater vehicle, mine countermeasures, guidance method, control system, information-measurement complex.

Yegorov S.A. (b. 1970) graduated from Bauman Moscow State Technical University in 1994. Ph. D., Head of Division of the Special Machinery Research Institute of Bauman Moscow State Technical University, author of more than 60 publications in the field of undersea robotics. e-mail: sa_egorov@mail.ru