

Des robots sous-marins à la recherche de Cordelière

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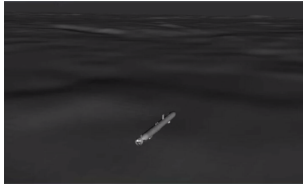


Etude avec les étudiants en robotique



Reconstitution de la bataille

youtu.be/yP4cM1UGrqY



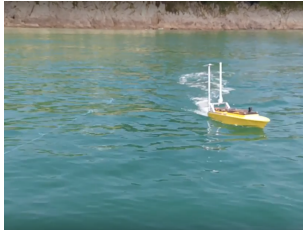
youtu.be/YAkUw1ggCvgA



[cordeliere.html](#)

[youtu.be/KXHyeWYGOI](#)

Submeeting

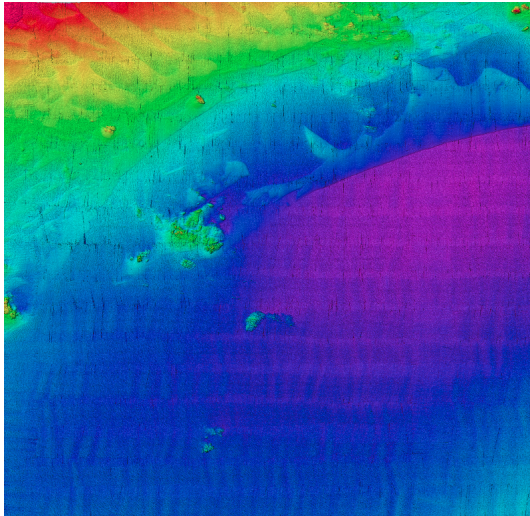


youtu.be/VqXG9zO_q1A

[submeeting2018.html](#)

22-23 mai 2018, Trez-Hir

Prochaine : 12-15 juin 2019, Trez-Hir





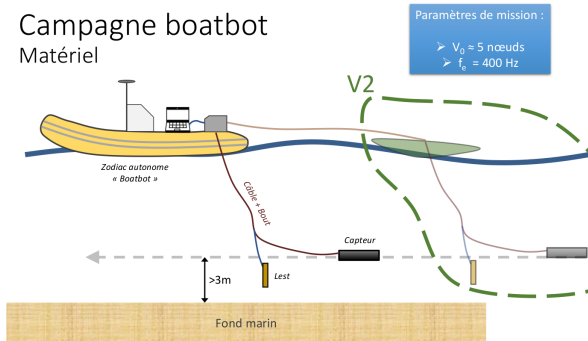
Magnétomètre

Objectif: remorquer le SeaSpy du Shom avec un robot (sous-marin ou surface).



Campagne boatbot

Matériel



Campagne boatbot Matériel

Capteur avant
« marinisation » :



Câble et bout

Lest

Capteur dans
son caisson étanche

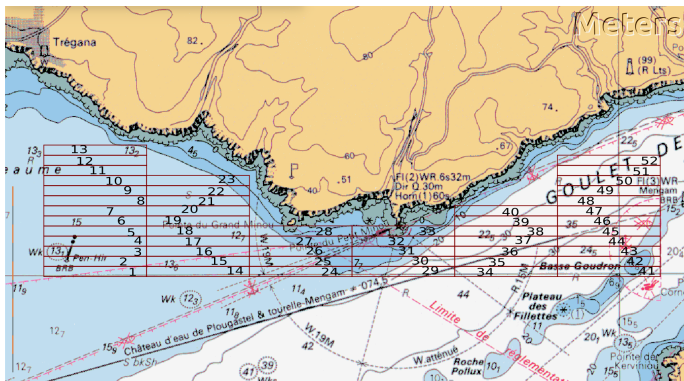


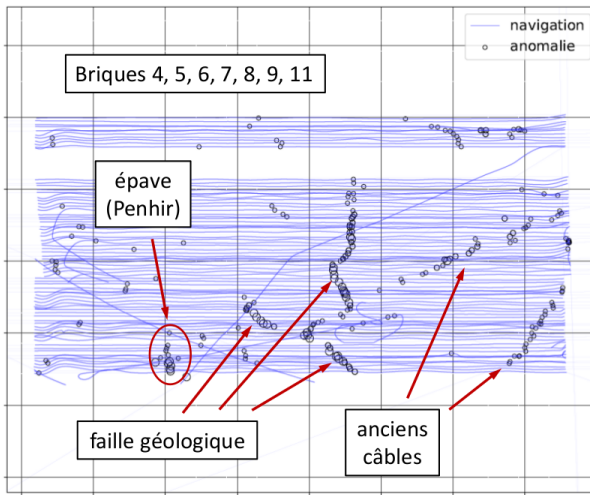
Boatbot





[boatbot.html](#)







Premières recherches avec Boatbot [2]

youtu.be/RSmUnKklfkM

[boatbot.html](#)

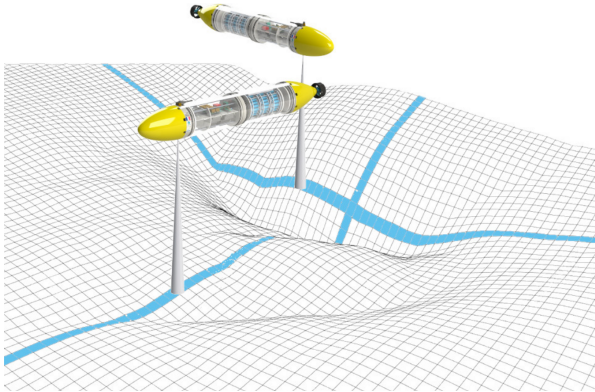


[moqesm2018](#)

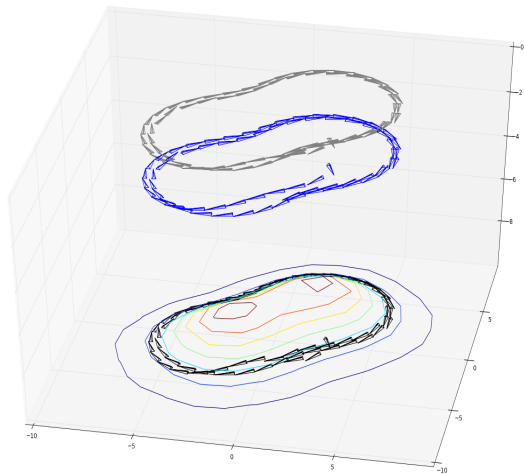
Boatbot ?
AUV ?

Exploration

- SLAM paradigm
- Bridge-river paradigm

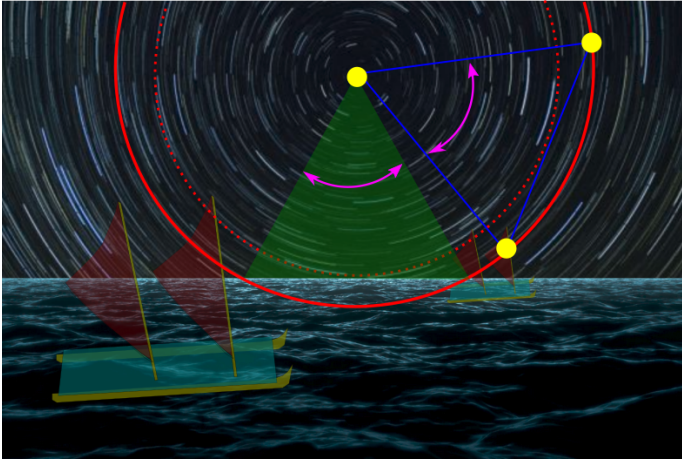


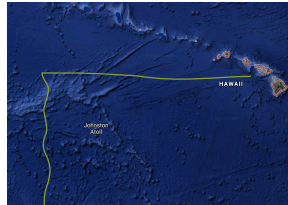
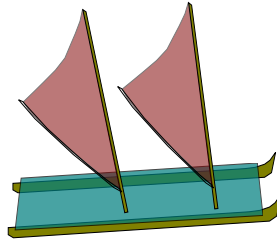
[3]





Find the route without GPS, compass and clock

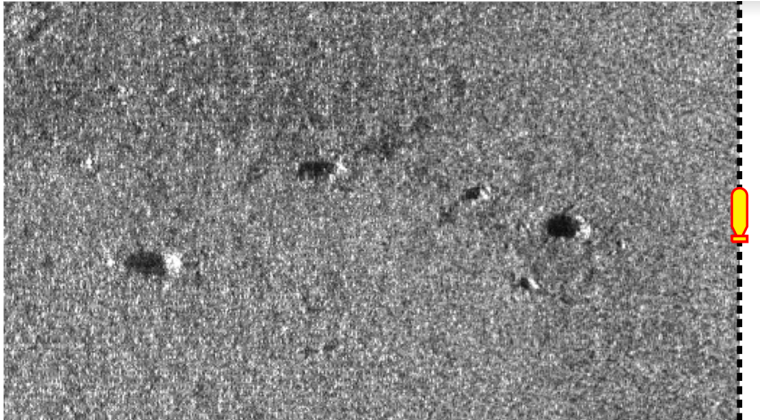




Thèse : Joris Tillet(DGA-Région), Julien Damers (CIFRE avec Kopadia)



Folaga





L. Jaulin.

Isobath following using an altimeter as a unique exteroceptive sensor.

In *IRSC-WRSC-2018, Southampton, 2018.*



L. Jaulin M. Le Gallic, J. Tillet and F. Le Bars.

Tight slalom control for sailboat robots.

In *IRSC-WRSC-2018, Southampton, 2018.*



S. Rohou.

Reliable robot localization: a constraint programming approach over dynamical systems.

PhD dissertation, Université de Bretagne Occidentale,
ENSTA-Bretagne, France, december 2017.