IPASJ International Journal of Electronics & Communication (IIJEC)
Web Site: http://www.ipasj.org/IIJEC/IIJEC.htm
A Publisher for Research Motivation ..... Email:editoriijec@ipasj.org
Volume 5, Issue 11, November 2017 ISSN 2321-5984

An accommodative formal logic figure scaled unscented Kalman filtering for direction system, GPS and gaussmeter sensors integration

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ABSTRACT

In this paper, we have a tendency to gift a way supported formal logic to enhance the performance of the direction system integrated with GPS, and gaussmeter. The planned fuzzy technique is primarily accustomed predict position and speed measurements throughout GPS outage signals. As long because the GPS measurements area unit out there, the Q-SUKF of INS/GPS/MAG (MAG: magnetometer) integrated system operates with efficiency and provides precise navigation states estimation. withal, throughout GPS outage signals, the planned fuzzy technique is tailored to the Q-SUKF to get the (A) (FL) QSUKF (Adaptive formal logic figure Scaled Unscented Kalman Filter) so as to correct the degradation of the performance of the algorithmic program. The accommodative formal logic attributes values to the measurements variance matrix so as to work out the gain of the filter. it'll decrease the measure noise variance of the Kalman filter and so improves eventually the accuracy of the integrated navigation system states estimation. Finally, Associate in Nursing experimental half on the utilization of the planned fuzzy technical with the Q-SUKF has been valid. many GPS outages with period of 30s are simulated to review the behavior of the planned filter. additionally, Associate in Nursing initial angle error of sixty degrees is given in every axis to check the hardiness of the filter planned below giant angle errors. The results of the experimental validation have shown the effectiveness and therefore the vital impact of the (A) (FL) Q-SUKF within the reduction of the drift errors estimation of the position and speed just in case of GPS outages within the tested eventualities.

1. INTRODUCTION

The low value direction systems offer correct and reliable navigation solutions after they area unit integrated with power-assisted sensors (GPS, magnetometer) within the filter QSUKF [1]. The INS/GPS/MAG integration is shortly classified as loosely-coupled, tightly-coupled and deeplycoupled. the selection of the mixing approach depends on the kind of application and on the operative surroundings. the big bias drift of mechanical phenomenon sensors stop the direction system to work in standalone mode and even once it's combined with the gaussmeter. Therefore, the performance of the integrated system can deteriorate significantly in periods of GPS outages. throughout the last decade, the Takagi-Sugeno (TS) fuzzy systems are accustomed model with success the non-linear systems and have tested an honest illustration of dynamic systems [2], [3], [4], [5]. In these approaches, the non linear behavior of a system is portrayed by a composition of "If-Then" rules, concatenating a collection of native linear sub models. during this article, a Takagi-Sugeno fuzzy model is employed to estimate the position and speed measurements to the integrated INS/GPS/MAG system throughout the varied GPS outages. The fuzzy model needs Associate in Nursing offline learning section extracted from an outsized range of input-output coupled knowledge once GPS signals area unit out there. This section aims to spot the parameters of the fuzzy model used with the filter Q-SUKF. The Input-Output knowledge cowl totally different dynamics and kinds of movement (straight and rotation). throughout the educational section, the inputs of the fuzzy model area unit position, speed and yaw angle expected by the Q-SUKF filter. The outputs of the fuzzy model area unit the positions and speed measured by the GPS. At the tip of the educational section, the simplest estimates of the parameters of the fuzzy model area unit achieved. Therefore, the model ought to be able to offer corrections or antagonistic measurements of position and speed throughout GPS outages in real time method. These measurements permit to take care of the update mode section of Q-SUKF fiter. during this paper, we have a tendency to describe a replacement pairing filter, (A) (FL) Q-SUKF, of those 3 sensors supported the applying of the fuzzy model with the Q-SUKF filter. Next, Associate in Nursing experimental half on the (A) (FL) Q-SUKF algorithmic program has been valid.

2. HARDINESS OF THE Q-SUKF

The Q-SUKF may be a algorithmic algorithmic program designed to correct the errors of the direction system through external measurements provided by power-assisted sensors that area unit here, the GPS and gaussmeter. As long because the GPS measurements area unit out there, the Q-SUKF operates with efficiency and provides a particular estimate of the navigation's states. withal, throughout the GPS outages, the general performance of INS/GPS or INS/GPS/MAG systems is considerably degraded attributable to the speedy accumulation of errors that have an effect on the mechanical phenomenon measure unit parts of the direction system.

2.1. Use of formal logic as a Criterion of hardiness of the Q-SUKF Filter

The formal logic may be a set of mathematical theories that deals with the illustration and manipulation of imperfect information (imprecise, unsure or incomplete). It doesn't obtain to eliminate them; on the contrary, it'll obtain to preserve to the most. Therefore, its purpose is to supple the illustration framework and knowledge's process, ennobling therefore from the human mental processes. the sensible applications of formal logic area unit varied. Examples include: response, robotics, professional systems, call support, etc. during this paper, the formal logic is outlined as a logic that uses the final perform of "expert system" in processing. A fuzzy model, denoted (A) (FL), is planned to resolve the matter of the performance's degradation of the INS/GPS or INS/GPS/MAG system throughout the GPS outages. once GPS signals area unit out there, this model is extracted offline from an outsized range of coupled input-output knowledge throughout a amount referred to as learning section. The inputs of the fuzzy model area unit, position, velocity, and yaw angles, expected by the Q-SUKF.

At the tip of the educational section, the simplest estimates of the parameters of the Fuzzy model area unit achieved. once Associate in Nursing outage GPS happens, the fuzzy model (A) (FL) generate alternately calculable measurements of position and speed and that area unit speculated to be the GPS measurements if they were out there. Consequently, the filter Q-SUKF continues to use the equations of measure update, as shown in Figure two. The Q-SUKF filter is noted (A) (FL) Q-SUKF once it's used with the planned fuzzy model.

3. PLANNED FUZZY ILLATION SYSTEM

The planned fuzzy model utilizes a fuzzy illation system of Takagi-Sugeno kind (FIS-TS) that has special properties since it represents the non-linear systems within the variety of Associate in Nursing interpolation between native linear models. The FIS-TS fuzzy model planned is written in a very general type as:

3.1. Determination of Antecedent Parameters

Abonyi in [6] has planned the Fuzzy C-Means classification algorithmic program (FCM) to spot the antecedent parameters of Takagi-Sugeno fuzzy model. The FCM algorithmic program aims to divide the information points into same categories or teams. Thus, the points within the same category area unit as similar as attainable whereas points in numerous categories area unit as dissimilar as attainable. The FCM algorithmic program, that issued from the works of [7] and improved later by [8], constitutes a vital reference among the differents strategies of fuzzy jointure [9] supported the minimisation of the target perform, of the form:

4. SIMULATIONS

In this section, the answer of the Q-SUKF filter used with the fuzzy model is bestowed. the most objective of the (A) (FL) Q-SUKF filter is to preserve the update section of the QSUKF filter by providing simulated measurements of position and speed throughout the GPS outages. The Fuzzy model is extracted from an outsized range of input/output knowledge through Associate in Nursing offline learning section. This learning section is realised throughout the supply or dependableness of GPS measurements. The inputs of the fuzzy system area unit the position, speed and therefore the yaw angle determined by the QSUKF filter. The outputs of the fuzzy model area unit the positions and velocities provided by the GPS. the educational section of fuzzy model is disbursed over a brief amount of your time between 2 serial GPS measurements. This ensures that the drift time of position and speed errors stay insignificant. It additionally ensures the dependableness of the measurements provided by the educational method. the variation of antecedent and resulting parameters of the fuzzy illation system throughout the educational method uses Fuzzy C-Means (FCM) classification and method of least squares Error (LSE) strategies severally. once GPS outage happens, the custom-made formal logic model (A) (FL) switches to the prediction mode to supply simulated measurements of position and speed to stay the correction innovate QSUKF filter. the matter now could be a way to attribute the values of the measurements provided by the planned fuzzy model to the variance matrix so as to work out the gain of the filter. to beat this downside, once the identification parameters of the fuzzy model area unit calculated, the calculable outputs

of the fuzzy model throughout the educational section area unit computed by applying the equation (eq.3). Note that the calculable outputs throughout the educational section embrace the result of the measurements noises of GPS as a result of they're calculated from the parameters of the fuzzy model known from these measurements. The variance of those calculable outputs area unit the diagonals components of the variance matrix that should be used because the error variance matrix of measurements of the fuzzy model throughout the GPS outages.

4.1. Simulation Model

To test the effectiveness of the (A) (FL)Q-SUKF filter and its impact on the accuracy of the navigation parameters calculation (specially the position and velocity), a simulated knowledge of mechanical phenomenon measure unit, GPS and gaussmeter were used. The experiment was conducted employing a automotive driving (reference trajectory) for thirty mimutes. This reference mechanical phenomenon was generated by the perform "progencar" of INS chest version three.0 created by GPSoft. This mechanical phenomenon covers totally different dynamic (static and kinematic) and eventualities of motion (rotations and rectilinear). the information of the direction system (angle and speed increments) were simulated from the parameters of the profile of the auto victimisation bound functions of the INS chest. These angle and speed increments are corrupted with numerous sources of errors like biases, scale factors Associate in Nursingd noises so as to come up with outputs near real knowledge of an direction system.

The GPS knowledge (position and velocity) were generated by adding to the positions and velocities knowledge of the reference mechanical phenomenon a Gaussian dissonance. The initial variance of the position expressed in mathematician coordinates within the navigation frame is capable two cm within the horizontal plane and is capable four cm within the vertical plane. The initial variance of the speed expressed within the navigation frame is capable zero.25 m/s for the horizontal parts and is capable zero.4 m/s for the vertical element. Simulated knowledge of the gaussmeter (Earth' s magnetic field) were generated within the navigation frame by the globe Magnetic Model 2010 (WMM-2010) that uses the geographic position of the vehicle to work out its parts. This reference field is remodeled into the body frame and corrupted by a Gaussian dissonance of zero-mean and variance capable zero,002 Gauss/s 1/2.
These 2 GPS outages are simulated to review the behavior of the (A) (FL) QSUKF filter within the case of degradation of the accuracy of GPS signals. totally different dynamics and kinds of movement (straight and rotation) are thought-about throughout these outages. The vehicule is turned ninety degree to the left once the primary GPS outage happens whereas the vehicle movement over the second outage of GPS was straight. In these two periods, the Q-SUKF filter operates in prediction mode and therefore the position and speed errors ought to increase with time. On the opposite hand, the planned methodology permits to our filter to work in update mode wherever the measurements of correction area unit obtained from the fuzzy model ((A) (FL) Q-SUKF).

We notice in these figures that the most errors of the position parts (δx ,δx et δx n e d) are reduced significantly when the applying of the planned technique of the fuzzy model to the Q-SUKF filter throughout the 2 periods of GPS outages. The table (Table 3) summarizes most|the utmost|the most} error and therefore the share of the reduction of this maximum error for the 3 position parts. The fuzzy model planned applied to the Q-SUKF filter has provides a big improvement of ninety five engaging at least within the reduction of the most errors on the various parts of the position.

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