

A Reinforcement Learning Approach to Control of a Quadrotor Biplane Tailsitter for Adaptive Landing Maneuvers

Jae Woo Kim
Ph.D. Student
Rensselaer Polytechnic Institute
Troy, NY, USA

Kristoff McIntosh
Ph.D. Student
Rensselaer Polytechnic Institute
Troy, NY, USA

Elena Shrestha
ORAU Postdoctoral Fellow
University of Michigan
Ann Arbor, MI, USA

Jean-Paul Reddinger
Aerospace Engineer
DEVCOM Army Research Laboratory
Aberdeen Proving Ground, MD, USA

Sandipan Mishra
Professor
Rensselaer Polytechnic Institute
Troy, NY, USA

ABSTRACT

This paper presents a reinforcement learning (RL) based trajectory planning and control architecture for autonomous landing maneuvers of a quadrotor biplane tailsitter (QRBP). The RL controller replaces a gradient-descent based optimal trajectory planner and outer loop position controller of a standard QRBP control system, while retaining the inner loop for regulating attitude dynamics. The RL agents are trained in a simulated environment, using a curriculum learning approach for training an RL agent capable of landing on a moving Unmanned Ground Vehicle (UGV) with changing velocity. The RL architecture is capable of generating landing trajectories onto a moving ground vehicle, with computational costs suitable for real-time implementation. Further, the RL guidance architecture successfully completes the landing mission more consistently compared to a gradient-descent based guidance architecture when there is uncertainty in the path of the UGV.

INTRODUCTION

Unmanned Aerial Systems (UASs) are seeing a growing interest as a technology that can overcome delivery, mobility, and sensing challenges for a variety of applications (Refs. 1, 2). While the majority of research and application has been focused on pure fixed wing or vertical take-off and landing (VTOL) platforms, an emerging research area involves transitioning, or hybrid UASs. These hybrid configurations incorporate the benefits of both fixed wing and VTOL aircraft, resulting in aerial vehicles that demonstrate the hovering and infrastructure-free takeoff/landing capabilities inherent to VTOL aircraft, alongside the efficient cruise operation and improved forward flight maneuverability inherent to fixed wing aircraft (Ref. 3). The tailsitter is a class of hybrid UAS that transitions between flight modes via a rigid body rotation, and is of particular interest due to the mechanical simplicity of the transition maneuver (Ref. 4). A specific example of a tailsitter UAV aircraft is the Quadrotor Biplane (QRBP), which incorporates two parallel wing sections mounted under four rotors in a quadrotor configuration (Ref. 5). The specific QRBP design used for this paper is the 3 lb. Common Research Configuration (CRC-3), which is depicted in Fig. 1.

The transition between flight regimes for tailsitter platforms involves complex aerodynamics, so a focus on autonomous guidance and control of the QRBP is vital for practical appli-



Figure 1: The 3 lb. Common Research Configuration (CRC-3) (Ref. 6)

cation of these platforms. This has been the focus of prior research efforts, such as in (Ref. 7) where Swarnkar *et al* designed a model-based control architecture based on both a quadrotor and fixed wing model approximation of the QRBP dependent on a mode-switching implementation, wherein different controllers are used to control the QRBP based on critical pitch angle. In (Ref. 8), a control architecture without

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Thomas Griffiths



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Table of Contents Reinforcement Learning For Autonomous Quadrotor Helicopter

1. Understanding the eBook Reinforcement Learning For Autonomous Quadrotor Helicopter
 - The Rise of Digital Reading Reinforcement Learning For Autonomous Quadrotor Helicopter
 - Advantages of eBooks Over Traditional Books
2. Identifying Reinforcement Learning For Autonomous Quadrotor Helicopter
 - Exploring Different Genres
 - Considering Fiction vs. Non-Fiction
 - Determining Your Reading Goals
3. Choosing the Right eBook Platform
 - Popular eBook Platforms
 - Features to Look for in an Reinforcement Learning For Autonomous Quadrotor Helicopter
 - User-Friendly Interface
4. Exploring eBook Recommendations from Reinforcement Learning For Autonomous Quadrotor Helicopter
 - Personalized Recommendations
 - Reinforcement Learning For Autonomous Quadrotor Helicopter User Reviews and Ratings

- Reinforcement Learning For Autonomous Quadrotor Helicopter and Bestseller Lists
- 5. Accessing Reinforcement Learning For Autonomous Quadrotor Helicopter Free and Paid eBooks
 - Reinforcement Learning For Autonomous Quadrotor Helicopter Public Domain eBooks
 - Reinforcement Learning For Autonomous Quadrotor Helicopter eBook Subscription Services
 - Reinforcement Learning For Autonomous Quadrotor Helicopter Budget-Friendly Options
- 6. Navigating Reinforcement Learning For Autonomous Quadrotor Helicopter eBook Formats
 - ePub, PDF, MOBI, and More
 - Reinforcement Learning For Autonomous Quadrotor Helicopter Compatibility with Devices
 - Reinforcement Learning For Autonomous Quadrotor Helicopter Enhanced eBook Features
- 7. Enhancing Your Reading Experience
 - Adjustable Fonts and Text Sizes of Reinforcement Learning For Autonomous Quadrotor Helicopter
 - Highlighting and Note-Taking Reinforcement Learning For Autonomous Quadrotor Helicopter
 - Interactive Elements Reinforcement Learning For Autonomous Quadrotor Helicopter
- 8. Staying Engaged with Reinforcement Learning For Autonomous Quadrotor Helicopter
 - Joining Online Reading Communities
 - Participating in Virtual Book Clubs
 - Following Authors and Publishers Reinforcement Learning For Autonomous Quadrotor Helicopter
- 9. Balancing eBooks and Physical Books Reinforcement Learning For Autonomous Quadrotor Helicopter
 - Benefits of a Digital Library
 - Creating a Diverse Reading Collection Reinforcement Learning For Autonomous Quadrotor Helicopter
- 10. Overcoming Reading Challenges
 - Dealing with Digital Eye Strain
 - Minimizing Distractions
 - Managing Screen Time
- 11. Cultivating a Reading Routine Reinforcement Learning For Autonomous Quadrotor Helicopter
 - Setting Reading Goals Reinforcement Learning For Autonomous Quadrotor Helicopter
 - Carving Out Dedicated Reading Time
- 12. Sourcing Reliable Information of Reinforcement Learning For Autonomous Quadrotor Helicopter
 - Fact-Checking eBook Content of Reinforcement Learning For Autonomous Quadrotor Helicopter
 - Distinguishing Credible Sources

13. Promoting Lifelong Learning
 - Utilizing eBooks for Skill Development
 - Exploring Educational eBooks
14. Embracing eBook Trends
 - Integration of Multimedia Elements
 - Interactive and Gamified eBooks

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