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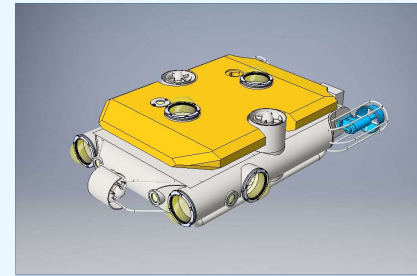
## 1 – Original ROV

- ❑ Very usable, lightweight, maneuverable underwater Remote Operated Vehicle (ROV)
- ❑ Diving down to 150 m depth
- ❑ Inspection of underwater electrical installation
- ❑ Umbilical cable is used to transfer data and electrical power
- ❑ Control by PS2 joystick console
- ❑ Developed by students and professors of the SOSS



## 2 – ROV under development

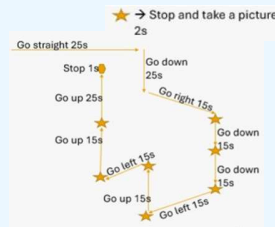
- ❑ Completely autonomous system (without cable)
- ❑ Battery powered - 2 x 625 Wh 36VDC
- ❑ Central control unit - ARK-1551-S6A1
- ❑ Dive control autopilot - Pixhawk 1
- ❑ Surface control system - computer, joystick, tether interface and screen
- ❑ Advanced communication to surface – Visible Light Communication (VLC) and ultrasound



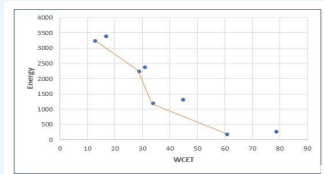
## 3 – Optimizing energy footprint

- ❑ Embed alternative hard/soft components for specific ROV mission achievement

Name	Task Type	Processor Name	Address Space	Capacity	Deadline	start time	Priority	Blocking T
GPS	Periodic	cpu1	ad1	2	10	0	1	0
data_encrypt	Periodic	cpu1	ad1	5	10	0	1	0
data_send	Periodic	cpu1	ad1	5	10	0	1	0
down1	Scheduling	cpu1	ad1	25	50	50	1	0



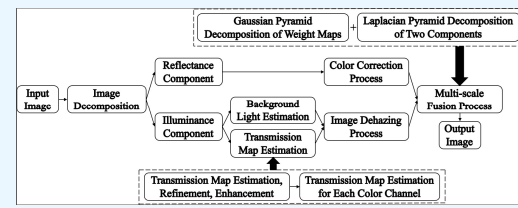
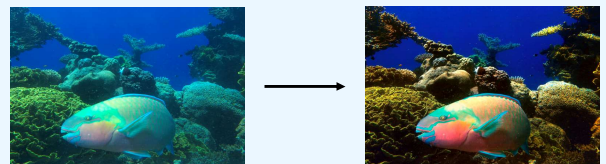
- ❑ Design Space Exploration : find trade-offs between schedulability (WCET) and energy for designs. *example of DSE options: lights, object recognition, DVFS*



- ❑ Use a multi objective optimization tool (PAES) coupled with an architecture simulator (Cheddar) for DSE of tasks scheduling

## 4 – Payload: image processing

- ❑ Underwater images are highly degraded
- ❑ Underwater vehicles need sight for auto positioning
- ❑ Five algorithms for underwater image restoration are compared and the best one is optimized
- ❑ Minimal execution time for real time applications



The general procedure of objects visibility enhancement process

- ❑ Implementation of 360° VR view in real time

This poster described the TARO project, a project funded by the ANR «Investissements d'avenir» number ANR-19-GURE-0001 in the framework of the ERASMUS+ SEA UE consortium