

# UAV Toolbox Release Notes



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### *UAV Toolbox Release Notes*

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# R2021b

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**Version: 1.2**

**New Features**

**Compatibility Considerations**

## Simulate UAV Scenarios Using Simulink

You can now use UAV scenarios to simulate systems and advance the simulation using Simulink® blocks:

- UAV Scenario Configuration — Import a `uavScenario` object and simulate the scenario.
- UAV Scenario Get Transform — Get a transform matrix that maps points in the source frame to the target frame.
- UAV Scenario Lidar — Simulate lidar measurements based on meshes in the scenario.
- UAV Scenario Motion Read — Read platform and sensor motions.
- UAV Scenario Motion Write — Update platform motion in the simulation.
- UAV Scenario Scope — Visualize scenario and lidar point clouds.

## GPS Sensor Block

Use the GPS block to simulate a GPS sensor with noise-corrupted measurements based on the input position and velocity. The block uses the WGS84 earth model to convert local coordinates to latitude-longitude-altitude (LLA) coordinates. You can vary the horizontal position, vertical position, and velocity accuracies to change noise levels in the output signals. Also, you can specify a decay factor, which models global position noise.

## INS Sensor Block

Use the INS block to model and simulate an INS sensor and generate INS measurements in Simulink.

## Video Streaming to UAV Hardware

The Video Send block sends a UDP video stream to a network address. Send images as a video feed to a hardware board, such as the NVIDIA® Jetson®, or other compatible GStreamer clients. You can send images captured by sensors in an Unreal® scenario for hardware-in-the-loop (HIL) simulation.

## Fixed-Wing UAV Point Mass Block

The Fixed-Wing UAV Point Mass block integrates the fourth- or sixth-order fixed-wing point mass equations of motion in coordinated flight.

## Obstacle Avoidance Block

Use the Obstacle Avoidance block to compute an obstacle-free direction using range sensor data and a target position.

## Minimum Jerk and Snap Polynomial Trajectories

Use the `minjerkpolytraj` function to generate a minimum jerk polynomial trajectory. Specify waypoints, time points, and number of samples to get a series of jerks, accelerations, velocities, and positions.

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Use the `minsnappolytraj` function to generate a minimum snap polynomial trajectory. Specify waypoints, time points, and number of samples to get a series of snaps, jerks, accelerations, velocities, and positions.

## Flight Log Analyzer App Enhancements

The **Flight Log Analyzer** app has been updated with these enhancements:

- The flight modes in the **Flight Modes** pane are now interactive. You can select one or more consecutive flight modes. The **Panner** limits values and adjusts handles accordingly.
- The **Signals** pane now displays the units of the signals.
- The axes labels of the plots are now customizable.
- You can now export multiple plots to a single figure or separate figures.

## Simulation 3D Environment Upgrade: Run 3D simulations using Unreal Engine, Version 4.25

The 3D visualization engine that comes installed with UAV Toolbox has been updated to Unreal Engine®, Version 4.25. Previously, the toolbox used Unreal Engine, Version 4.23.

For information about using Unreal Engine to create custom scenes, see “Customize Unreal Engine Scenes for UAVs”.

## Compatibility Considerations

If your Simulink model uses an Unreal Engine executable or project developed using a prior release of the UAV Toolbox Interface for Unreal Engine Projects support package, the simulation might produce an error. To migrate the project so that it is compatible with the R2021b version of the support package, see “Migrate Projects Developed Using Prior Support Packages”.

## Simulation 3D Environment Performance Improvements: Run 3D simulations faster than real-time

Simulink co-simulations with Unreal Engine can run faster than real-time. Previously, the Unreal Engine frames-per-second (FPS) was limited by the inverse of the *simulation* sample rate. If you want to slow down a 3D simulation to investigate the system behavior, you can still use simulation pacing.

To control simulation time, use the Simulation 3D Scene Configuration block parameter **Sample time**. For example, if **Sample time** is  $1/30$ , then the visualization engine solver tries to achieve a *minimum* frame rate of 30 fps. However, the real-time graphics frame rate is often lower due to factors such as graphics card performance and model complexity. With reasonable graphics card performance and less model complexity, the fps could be greater than 30, not limited to 30 as it was in previous releases.

## Position Adjustments of Unreal Engine Cameras: Update relative translation and rotation of camera sensors during simulation

In the Simulation 3D Camera and Simulation 3D Fisheye Camera blocks, use the **Translation** and **Rotation** input ports to update the position of the cameras relative to their mounting positions

during simulation. You can use these position adjustments to better model actuator dynamics, isolation mounting, and calibration workflows.

Previously, you could set only constant relative positions by using the **Relative translation [X, Y, Z] (m)** and **Relative rotation [Roll, Pitch, Yaw] (deg)** parameters. Now, by selecting **Input** to enable the corresponding ports, the parameters specify the initial position and the ports specify the position during simulation.

## Unreal Engine Vehicle Enhancements: Import custom meshes

You can configure the Simulation 3D UAV Vehicle block to import custom meshes using this process:

- 1 Install the UAV Toolbox Interface for Unreal Engine Projects support package. See “Install Support Package for Customizing Scenes”.
- 2 On the block **Parameters** tab, set **Type** to Custom.
- 3 In the **Path to custom mesh** field, enter the path to the vehicle mesh in the Unreal Engine project. To create a custom vehicle mesh, see “Prepare Custom UAV Vehicle Mesh for the Unreal Editor”.
- 4 Use the vehicle dimensions in the custom mesh to enter the dimensions in the corresponding block parameter fields.



# R2021a

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**Version: 1.1**

**New Features**

## **Terrain and Mesh Support in UAV Scenarios: Add DTED terrain data or meshes to simulated UAV scenarios**

Load digital terrain elevation data (DTED) using the `addCustomTerrain` function, and add the terrain to the UAV scenario using the `addMesh` function.

To specify complex mesh objects as triangulated vertices and faces, use the `extendedObjectMesh` object. Add the mesh to UAV scenarios using the `addMesh` function.

## **Custom Sensor Support in UAV Scenarios: Add custom sensor models to UAVs in simulated scenarios**

Specify custom sensor models and define their behavior in simulation using the `uav.SensorAdapter` class. To generate a template for implementing the class, use the `createCustomSensorTemplate` function.

## **Flight Log Analyzer Update on Signal Export: Export signals as timetables to the MATLAB workspace or a MAT-file**

The **Flight Log Analyzer** app now enables you to export signals as timetables to the MATLAB workspace or a MAT-file. To export signals, select **Export > Export Signal**. In the **Export Signal** dialog box, select the listed signals you want to export, select the export format, and click **Export**.

## **Flight Log Signal Mapping Object Update: Check mapped signals using flight log data**

Use the `checkSignal` object function of the `flightLogSignalMapping` object to verify mapped signals using the flight log data.

## **Unreal Engine Scene Environment: Control weather and sun position**

Use the Simulation 3D Scene Configuration block to control scene weather and sun position. Options allow you to create realistic environments when you run maneuvers and test control algorithms in the Unreal Engine 3D simulation environment. The Simulation 3D Camera and Simulation 3D Fisheye Camera blocks receive the image from the 3D simulation environment.

To control scene weather and sun position, on the Simulation 3D Scene Configuration block **Weather** tab, select **Override scene weather**. Use the enabled parameters to change the sun position, clouds, fog, and rain during the simulation.

# R2020b

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**Version: 1.0**

**New Features**

## **UAV Scenarios and Sensor Models: Construct cuboid scenario and simulate sensor readings for UAV applications**

The `uavSensor` object generates a simulation scenario consisting of static meshes, UAV platforms, and sensors in a 3D environment. Add `uavPlatform` objects to the scenario and attach different sensor models with the `uavSensor` object.

The `uavPlatform` object represents an unmanned aerial vehicle (UAV) platform in a given UAV scenario. Use the platform to define and track the trajectory of an object in the scenario. To simulate sensor readings for the platform, mount sensors like the `gpsSensor`, `insSensor`, or `uavLidarPointCloudGenerator` objects with a set of `uavSensor` objects. Add a body mesh for visualization using `updateMesh`. Set geofencing limitations using `addGeoFence` and check those limits using `checkPermission`.

The `uavSensor` object creates a sensor that is rigidly attached to a UAV platform, specified as a `uavPlatform` object. You can specify different mounting positions and orientations. Configure this object to automatically generate readings from a sensor specified as an `insSensor`, `gpsSensor`, or `uavLidarPointCloudGenerator` object.

For an introduction to scenarios, see [UAV Scenario Tutorial](#).

## **3D Simulation: Develop, test, and verify UAV algorithms in a 3D simulation environment rendered using the Unreal Engine from Epic Games**

UAV Toolbox provides a co-simulation framework that models driving algorithms in Simulink and visualizes their performance in a virtual simulation environment. This environment uses the Unreal Engine from Epic Games®.

For an introduction to 3D simulation, see [Unreal Engine Simulation for Unmanned Aerial Vehicles](#).

## **Flight Log Analyzer App: Import and visualize autopilot flight log with pre-defined and customizable plots**

To analyze a log file and create a customized series of plots, use the **Flight Log Analyzer** app.

Flight logs for UAVs contain large amounts of data with many varying formats. Use the flight log analysis functions to load different telemetry log files including TLOG, ULOG, and custom file types. To extract and map signals from a telemetry log for generating plots, use the `flightLogSignalMapping` object.

For more information, see [Flight Log Analysis](#).

## **UAV Motion Planning and Control: Design and simulate autonomous missions for fixed-wing and multirotor UAV with waypoint following, orbiting, and path management**

Plan and execute UAV flights using guidance motion models for fixed-wing and multirotor UAVs. Fly predefined missions using waypoint and trajectory following algorithms.

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For an example using an RRT path planner that plans and simulates a flight in a city setting, see **Motion Planning with RRT for Fixed-Wing UAV** .

For more information, see Planning and Control.

## **MAVLink Connectivity and Deployment: Communicate with UAV hardware using the MAVLink protocol and deploy to target hardware**

The Micro Air Vehicle Link (MAVLink) communication protocol is a message protocol for sending and receiving messages between UAVs. The protocol uses a publish-subscribe pattern for data streams with specified topics and message types. There are different sub-protocols for missions and parameters. Use the MAVLink supported functions or blocks to specify predefined or custom dialects, setup clients, and send or receive messages.

## **UAV Reference Application: Use a reference model to simulate and test UAV package delivery with obstacle avoidance**

For this reference application, see the UAV Package Delivery example.

## **UAV Toolbox Support Package for PX4 Autopilots: Build and deploy flight control algorithms to the Pixhawk Autopilot**

For more information, see UAV Toolbox Support Package for PX4 Autopilots.

