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Cross body thrusters permit a body of revolution Autonomous Underwater Vehicle to retain the energy efficiency of forward travel while increasing the ability to maneuver in confined areas such as harbors and piers. This maneuverability also permits more deliberate underwater surveys using a fixed, mounted forward and downward looking sonar.

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Performing a thruster engages both upper and lower body muscles such as the quads, hamstrings, glutes, abs, back, shoulders, and even the triceps. Typically done with a barbell, you can also use dumbbells, kettlebells, and even sandbags. It

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The kettlebell thruster offers many of the same benefits as the dumbbell thruster, working each side of the body separately to expose and correct any weaknesses, but there are a couple of reasons ...

How To Do The Thruster | Coach

The thruster is essentially a full-body move with emphasis placed on the quads, glutes, core, and shoulders. One great feature of the thruster is that you can perform it with many different pieces of equipment — for instance, kettlebells and dumbbells work just as well as the barbell variation prescribed in the famed Fran benchmark workout.

Thruster Up for A Full Body Blast | Muscle & Fitness

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Cross body thrusters permit a body of revolution Autonomous Underwater Vehicle to retain the energy efficiency of forward travel while increasing the ability to maneuver in confined areas such as harbors and piers. This maneuverability also permits more deliberate underwater surveys using a fixed, mounted forward and downward looking sonar. This work develops the necessary hydrodynamic coefficients, using methods applied to earlier vehicles, to develop a valid computer simulation model. Additionally, this work develops a polynomial regression translating thruster input in RPM to an applied force output, which is incorporated into the vehicle model. This model is then employed to examine the response and control, specifically at low speed, of a body-of-revolution Autonomous Underwater Vehicle equipped with off-axis cross-body thrusters. These results are then utilized to develop a series of PID controllers for use onboard the REMUS Autonomous Underwater Vehicle.

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Ireland is a small Island in the North Atlantic with geography, weather and thus way of life dominated by the ocean. This book presents a comprehensive study of the challenges and technologies for observing the ocean environment. It describes the state-of-the-art in marine platforms internationally and provides a vision of platform technology in 2021 and beyond. Opportunities for ocean monitoring are detailed in the Irish context and recommendations are given for future development and investments in marine platforms.

The objective of the program was to develop the technology and demonstrate the use of linear discrete actuators combined with a rocket control system (RCS) to control the large angle slew and fine pointing/tracking of a simulated large flexible space structure. The linear actuators included proof-mass actuators, and a hub torquer to simulate a control moment gyro or reaction wheel actuator. The demonstration used the CSDL/AFAL ground test facility located at CSDL, Inc. The facility comprises the flexible test structure and actuators which are mounted on a low-friction, air-bearing table, and associated test instrumentation. The combined linear discrete and RCS actuators demonstrated significantly improved fine pointing/tracking a vibration suppression capability relative to the uses of the RCS alone. Keywords include: Linear discrete actuators, Proof-mass actuators, and Flexible structure control. (rh).

The Odyssey IV class AUV was designed to fill the evolving needs of research and industry for a deep rated (6000 meter) vehicle, which is capable of both efficient cruising and precise hovering.

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This AUV is powerful enough to reject currents typical in the open ocean environment and yet small enough to be deployed from a small fishing boat. The thruster layout, two vectored side thrusters and two fixed cross-body thrusters, allow for 4-DOF control, which gives this vehicle precision and flexibility not possible in previous Odyssey class AUVs. An adaptable payload area allows the mounting of sensors, actuators, or other hardware suitable to a particular mission. The dynamic control layer of our behavior-based MOOS software was completely redesigned to take advantage of the capabilities of this vehicle. This is also the first platform to utilize new graphical controls and database-driven logging which increase operator efficiency and make the vehicle safer to operate. Odyssey IV's intended uses include survey and inspection of cold water corals, fisheries, archaeological sites, and subsea infrastructure. It will also serve as a research platform for computer vision-based servoing and acoustic supervisory control. This paper will document the design considerations and implementation of the Odyssey IV, as well as report on a series of field tests culminating in its first scientific deployment at Georges Bank, observing and mapping the invasive tunicate *Didemnum*.

The papers presented in this volume cover recent progress in applications of new theory on manoeuvring-related problems for surface ships and control and sensor problems for underwater vehicles.

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