**PROJECT OVERVIEW**

The completion of this AUV (Autonomous Underwater Vehicle) will allow for underwater research using long distance acoustic methods.

**Requirements:**
- AUV must have the ability to maneuver in 3D underwater space
- AUV must be autonomous and be able to move on a predefined path using integrated sensors.
- The AUV must have a rotating hydrophone array capable of acoustic research.

**MEET THE TEAM: AUV PATHFINDERS**

- Tristan Arenzana: ME: Manufacturing
- Alan Gonzalez: ME: Quality Lead
- Richard Brillantes: ME: Design Lead
- Brenden Ludkevicz: CE: Project Lead
- Steven Sanchez: CE: Coding Lead

**ACKNOWLEDGEMENTS**

Team AUV Pathfinders would like to thank Dr. Scott Shaffar and Professor Barry Dorr for advising us through this senior design project. We would also like to thank our sponsor, Dr. Zahra Nili Ahmadabadi for funding and providing guidance for our project.

**AUTONOMOUS UNDERWATER VEHICLE FOR PASSIVE SONAR**

**SYSTEM LEVEL DIAGRAM**

**ANALYSIS**

Condition Created To analyze drag on the faces of the full AUV Frame Assembly.

- 0.5 m/s = 20.4 N
- 1 m/s = 20.9 N
- 2 m/s = 22.4 N

**TEST METHODS**

Testing methods include electronics testing and ensuring that all electronics are properly integrated. After all electronics are integrated, water proof and buoyancy testing is performed. These tests allow the team to verify all project objectives.