

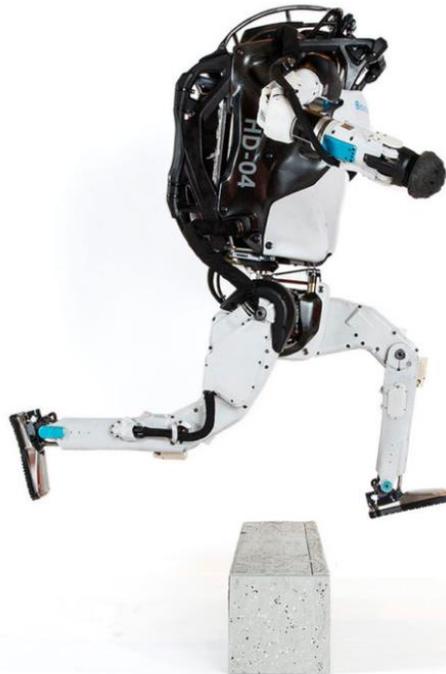
Robotics and Drones program at Vattenfall

Vattenfall R&D

Anders Wik

2022-06-02

What is a robot?



Introduction

Location of our operations and major plants

Click on energy source to show locations



Wind ●



Biomass ●



Hydro ●



Gas ●



Nuclear ●



Coal ●

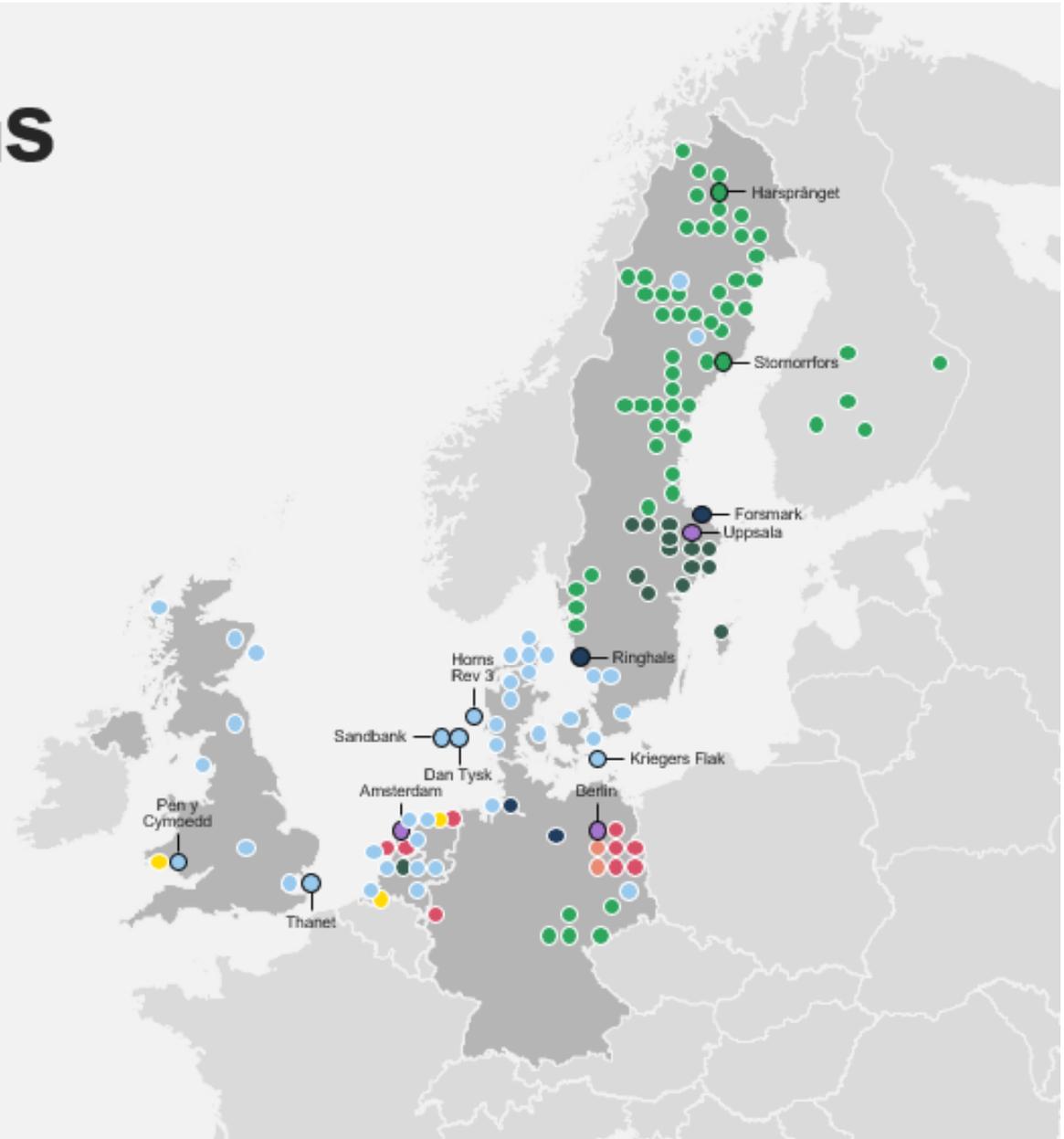


Solar ●



District heating ●

○ Largest facilities marked with a circle



Following equipment is used (examples)

Vehicles

- Drones >200 drones in operation
- ROV's ("submarines") 5 ROV in operation
- Spot Mini ("Robot Dog") 1 in early test phase

Payloads

- Sonars
- Optical and thermal cameras
- Stereo camera with slam
- Radiation meters



R&D Strategy Digital Inspections

Approved by Company IT

Deployment

Technology evaluation (Market)

Qualified inspections

Drones

ROV

Spot Mini

Sensor systems

Smart Cameras

Sensors

Total infrastructure

Digital Inspection Lab

Build

Content

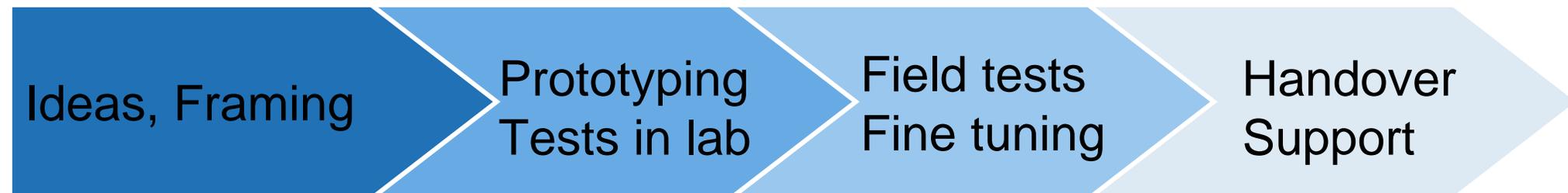
Autonomous systems

Airbased

Groundbased

Workflow R&D towards deployment

- Ideas are framed and goes through a screening process for Go/No Go
- Prototypes are produced and tested in lab environment
- Field tests are conducted to see robustness and user friendliness
- Finally product/service is handed over to BA/BU for deployment. Support function remains for a certain time period by R&D



The colours indicate the involvement of R&D. The darker, the more involvement from R&D personnel and laboratory resources.

Training of site security personnel at NPP 2021



Work tasks:

- Perimeter surveillance
- Crowd monitoring
- Monitoring of sensitive assets
- Etc.

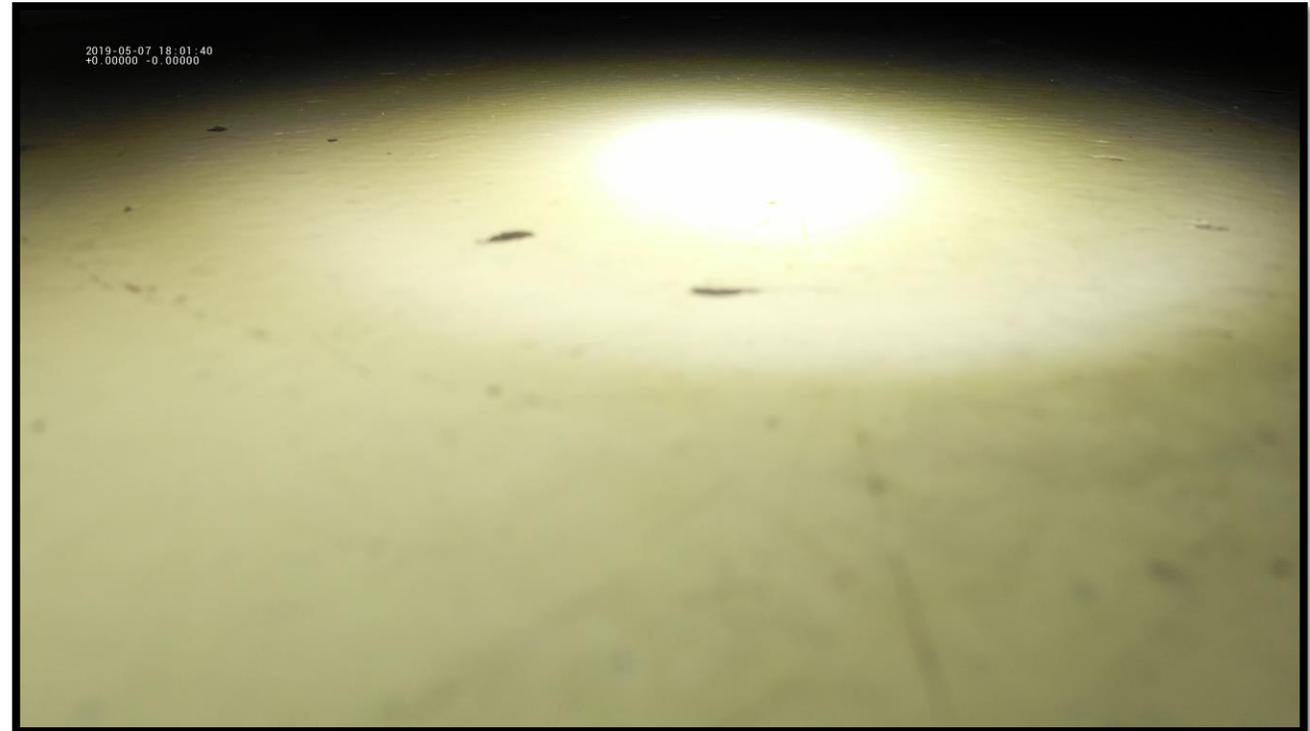
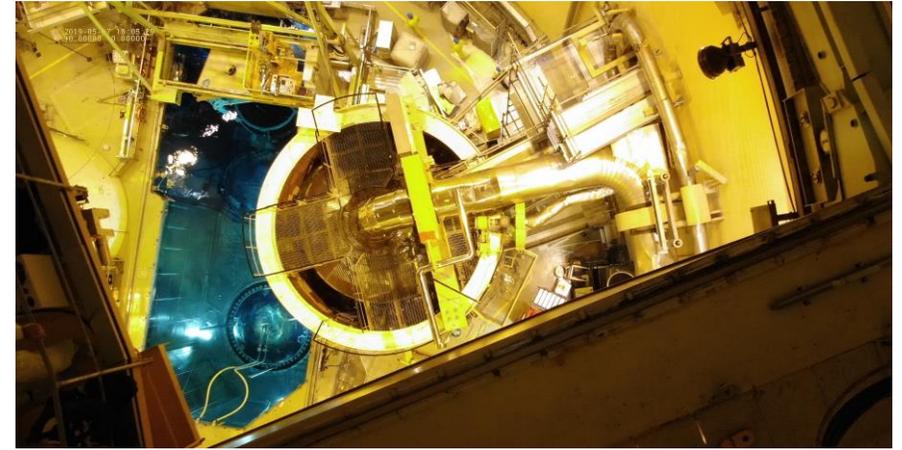
Training:

- Handling of equipment
- Risk reduction
- Practical flight training

7

Dome liner inspection

- Inspections traditionally done with personnel on polar crane using a camera on a "selfie stick".
- With drones you shorten the time, you avoid work hazards and can do it "on-the-fly" with experts looking at video.



Drone inspection in BWR NPP 2021



- Drones makes inspections and monitoring possible at full load within the turbine island in BWR – Minimize dose and may also give the possibility to continue operate at full power
- In near future...
 - ...Scheduled rounds possible in high radiation zones
 - ...Radiation maps done with drone system

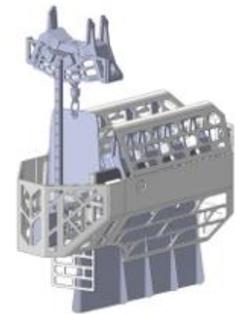
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Customized vehicles #1

Birdflapper

- Device for putting up "scare crows"
- Commercial drone
- 3D-printed parts
- In house programming
- Tests in lab 2021
- Deployed 2022

[Birdflapper - Vattenfall RnD DigIn in cooperation with Vattenfall Service. – YouTube](#)



Customized vehicles #2

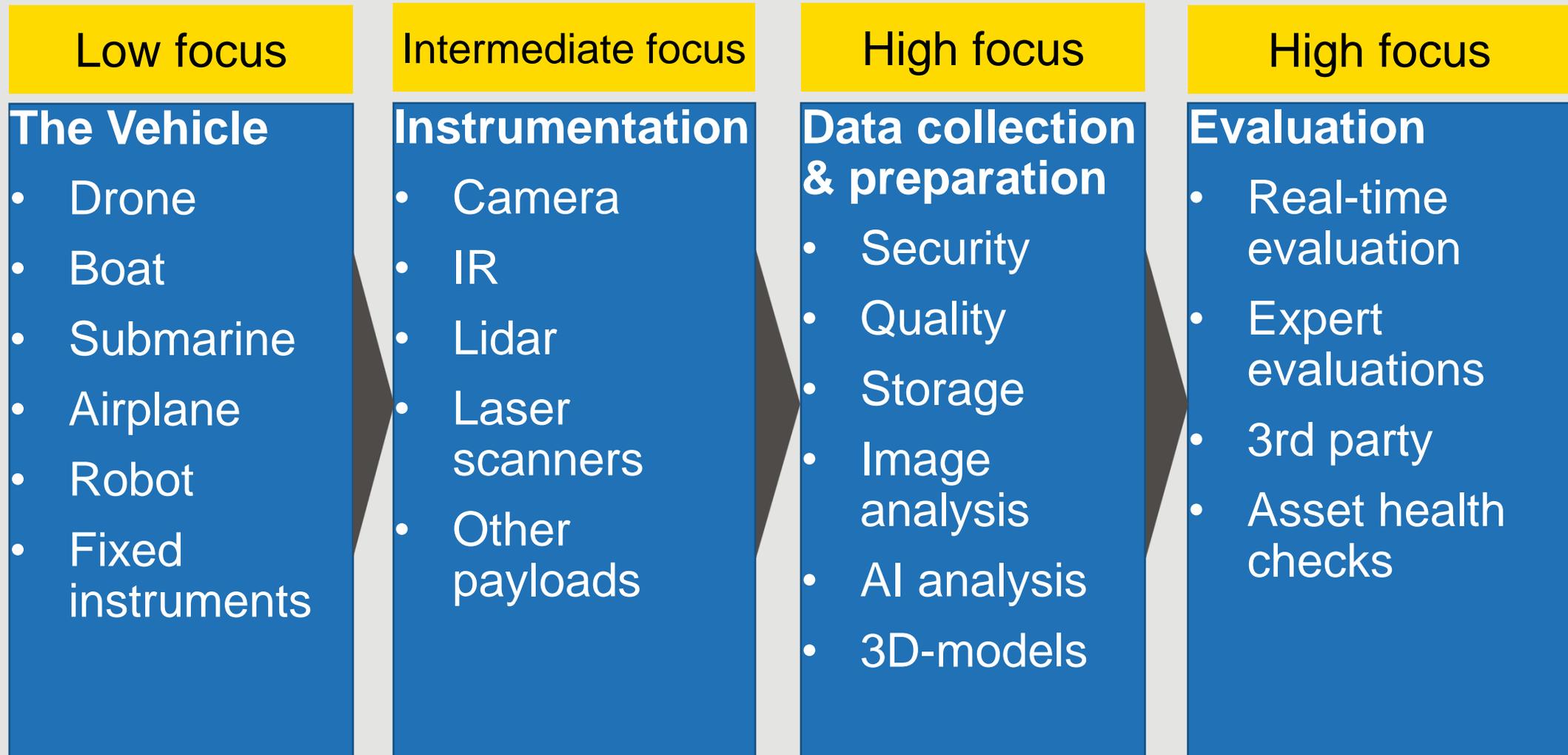
- Mini Sonar Boat
- RC car Welding Scanner

- Mini sonar boat for scanning shallow water in hydro power applications.
- The welding scanner is used for QA of windpower monopiles.
- The programming is done in-house for both vehicles.



```
263
264 /**
265  * @details Calculates the parameters of toe radius for a given circle_tangent value, assuming the circle is tangent to both vertical and horizontal tang
266  * circle_tangent is the distance between the tangents intersecting point and the points of tangency, also named "l" in the standards.
267  * center_to_intersect is the total distance between the circle center and the intersecting point between the tangents.
268  * bisector_angle values are used for calculating center position x0,y0.
269  *
270  * @param circle_tangent
271  * @param vtang
272  * @param b_angle
273  * @return ToeRadius
274  */
275 ToeRadius CalculateToeRadius(const double circle_tangent, const Tangent vtang, const BisectorAngle b_angle)
276 {
277     ToeRadius r;
278     r.circle_tangent = circle_tangent;
279     r.radius = std::abs(r.circle_tangent * std::tan(b_angle.bisector));
280     r.center_to_intersect = r.circle_tangent / std::cos(b_angle.bisector);
281     r.center_x0 = vtang.tangent_intersect.x + r.center_to_intersect * std::cos(b_angle.bisector_to_horizontal);
282     r.center_y0 = vtang.tangent_intersect.y + r.center_to_intersect * std::sin(b_angle.bisector_to_horizontal);
283
284     return r;
285 }
286
287 /**
288  * @details Searches for the nearest neighbours around the toe's second derivate peak, named "toe" here.
289  * Creates a vector storing the distance of each profile point to the toe with the same index as profile points list.
290  * A list a neighbours is created by keeping only the closest points, aka neighbours with lowest distance.
291
```

Digital inspections value chain



Autonomous inspections

Numerous use cases within all of our generation assets

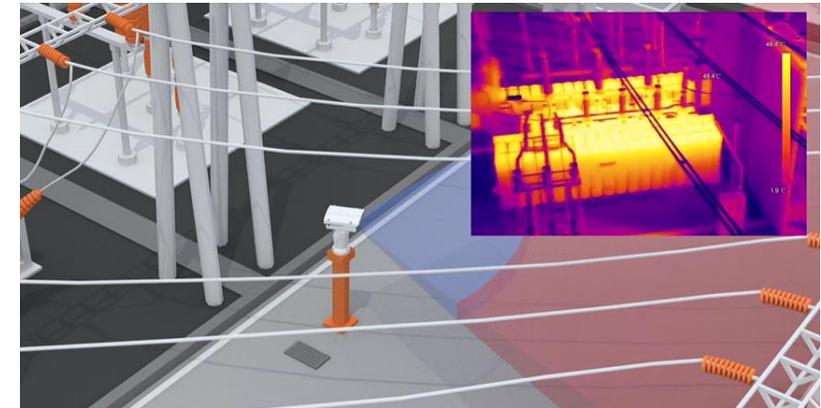
Aerial ("Drone in a box") and Ground based (Spot Mini)

- Rounding
- Scanning
- Security (perimeter inspections)
- Many other use cases for hydropower, distribution etc

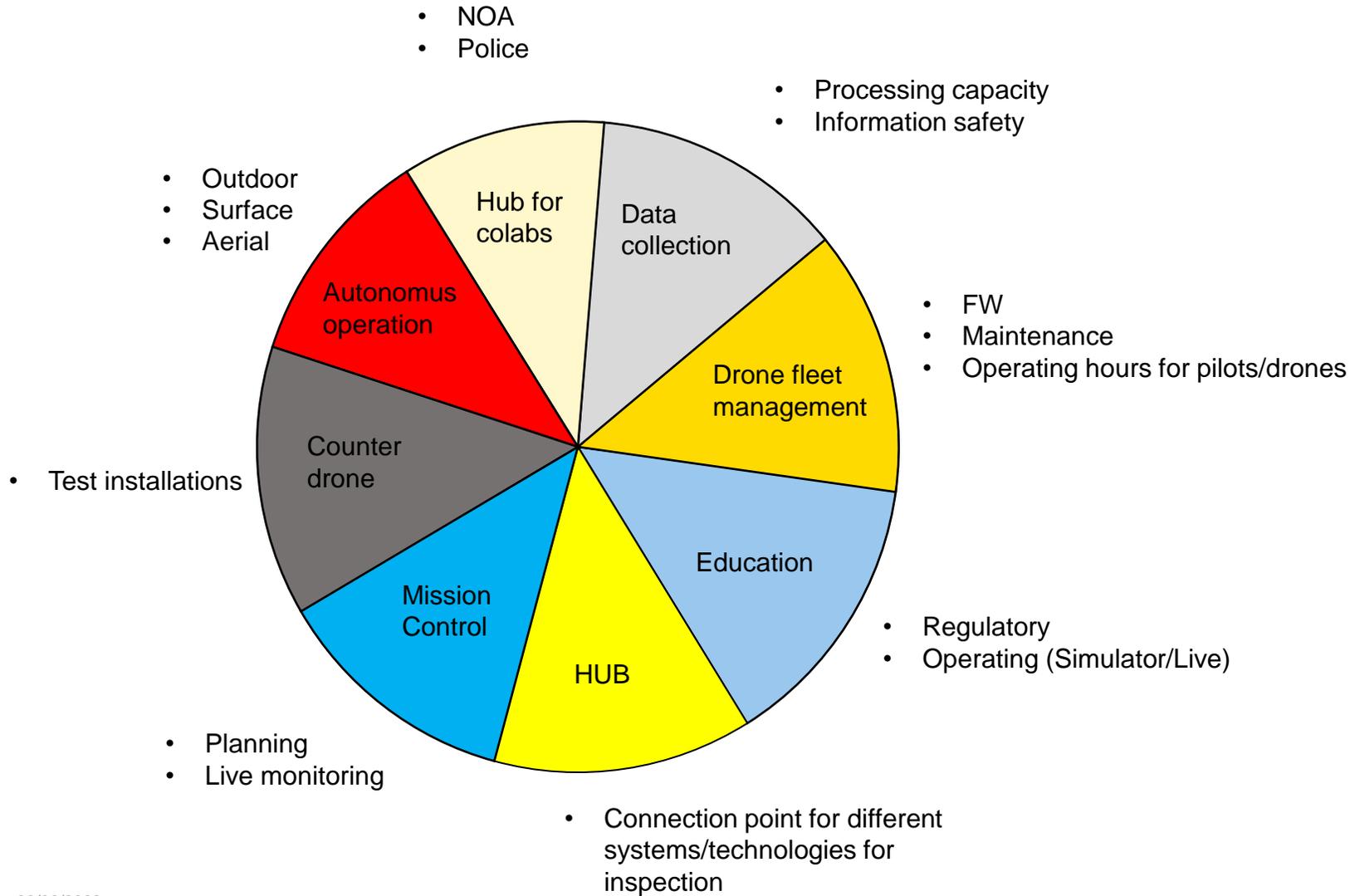


Robotics and AI, future work

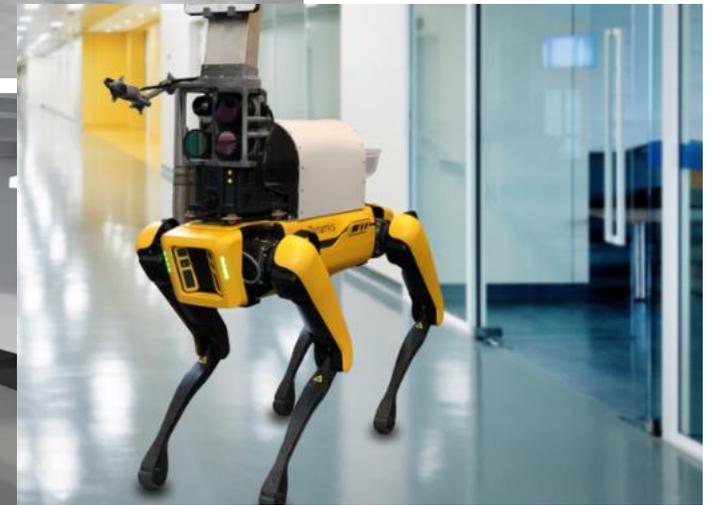
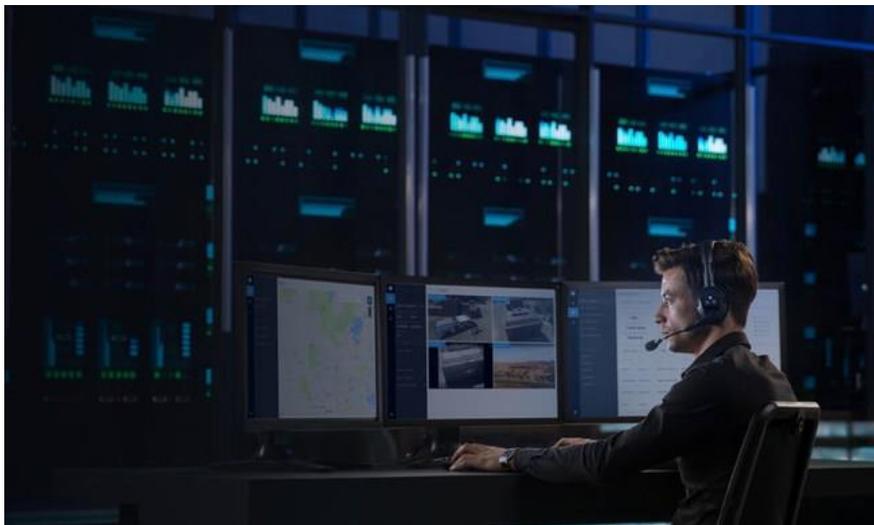
- Image recognition, simple
- Image recognition, advanced
- Spot Mini ("Robot Dog") in early test phase



What is needed for success?



DIL Digital Inspection Laboratory (Operable Q3 2022)



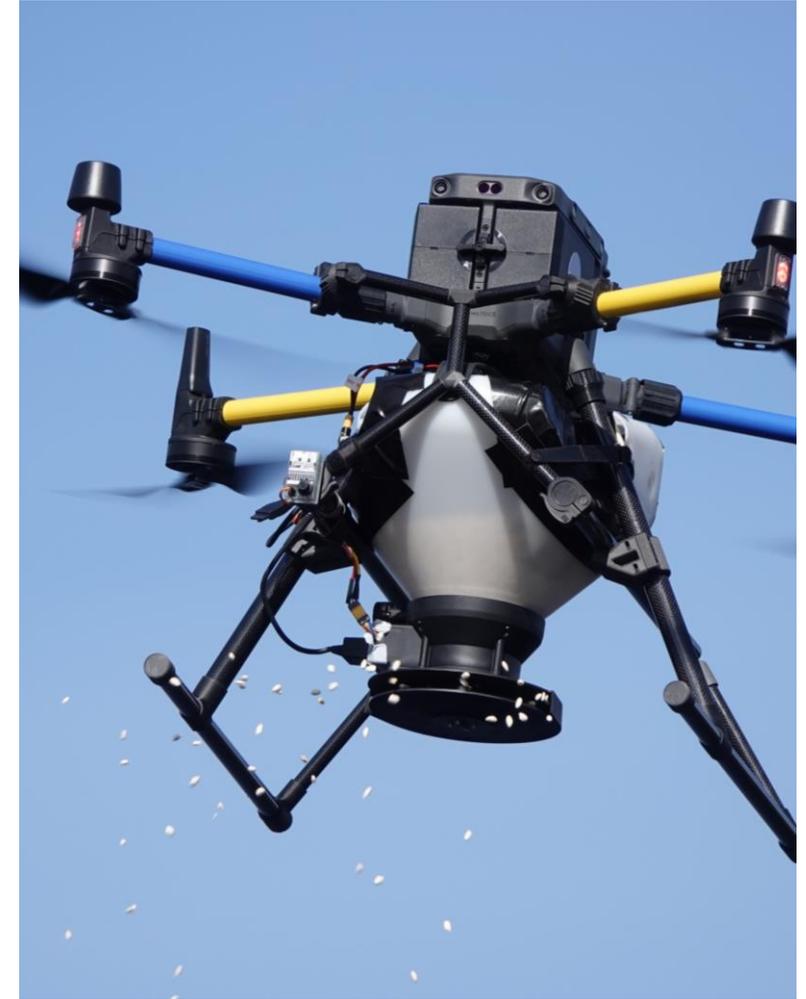
Lessons learned so far with Drones and Robots

Challenges

- Information security
- Organisational challenges
- Wide variety of services or solutions out on the market – Chose carefully!
- Chinese drones/technology – Who to trust!

Success factors

- A team with high competence when it comes to technology but also a network within the company.
- We have been given the opportunity to do real live tests!
- A good business case for our use cases (more safe, more efficient and with higher quality)



Thank You for Your Attention

Deployment Strategy, from R&D to Business Units operations

