



## Standard Guide for Unmanned Undersea Vehicle (UUV) Physical Payload Interface<sup>1</sup>

This standard is issued under the fixed designation F2545; the number immediately following the designation indicates the year of original adoption or, in the case of revision, the year of last revision. A number in parentheses indicates the year of last reapproval. A superscript epsilon ( $\epsilon$ ) indicates an editorial change since the last revision or reapproval.

### INTRODUCTION

ASTM has prepared this series of standards to guide the development of autonomous unmanned underwater vehicles (UUVs). The standards address the key capabilities that a UUV system must possess in order to be considered autonomous and reconfigurable:

*Autonomous*—Capable of operating without operator input for extended periods of time. Implicit in this description is the requirement that the UUV's sortie accomplishes its assigned goal and makes the appropriate rendezvous for a successful recovery.

*Reconfigurable*—Capable of operating with multiple payloads.

The top level requirement is established that the UUV systems will consist of:

*Payloads* to complete specific system tasking such as environmental data collection, area surveillance, mine hunting, mine countermeasures, intelligence/surveillance/reconnaissance (ISR), or other scientific, military, or commercial objectives.

*Vehicles* that will transport the payloads to designated locations and be responsible for the launch and recovery of the vehicle/payload combination. While the payload will be specific to the objective, the vehicle is likely to be less so. Nevertheless, commonality across all classes of UUV with respect to such features as planning, communications, and post sortie analysis (PSA) is desirable. Commonality with regard to such features as launch and recovery and a common control interface with the payload should be preserved within the UUV class. In accordance with this philosophy, ASTM identifies four standards to address UUV development and to promote compatibility and interoperability among UUVs:

- F2541 Guide for UUV Autonomy and Control,
- F2545 Guide for UUV Physical Payload Interface,
- F2594 Guide for UUV Communications, and
- F2595 Guide for UUV Sensor Data Formats.

The relationships among these standards are illustrated in Fig. 1. The first two standards address the UUV autonomy, command and control, and the physical interface between the UUV and its payload. The last two ASTM standards address the handling of the most valuable artifacts created by UUV systems: the data. Since there are many possibilities for communications links to exchange data, it is expected that the UUV procurement agency will provide specific guidance relative to these links and the appropriate use of the UUV communications standard. In a similar manner, specific guidance is expected for the appropriate use of the UUV data formats.

*F2541 Standard Guide for UUV Autonomy and Control*—The UUV autonomy and control guide defines the characteristics of an autonomous UUV system. While much of this guide applies to the vehicle and how the vehicle should perform in an autonomous state, the relationship of the payloads within the UUV system is also characterized. A high level depiction of the functional subsystems associated with a generic autonomous UUV system is presented. The important functional relationship established in this guide is the payload's subordinate role relative to the vehicle in terms of system safety. The payload is responsible for its own internal safety, but the vehicle is responsible for the safety of the vehicle-payload system. Terminology is defined to provide a common framework for the discussion of autonomous systems. System behaviors and capabilities are identified that tend to make a system independent of human operator input and provide varying levels of assurance that the UUV will perform its assigned task and successfully complete recovery. A three-axis sliding scale is presented to illustrate the system's level of autonomy (LOA) in terms of situational awareness,