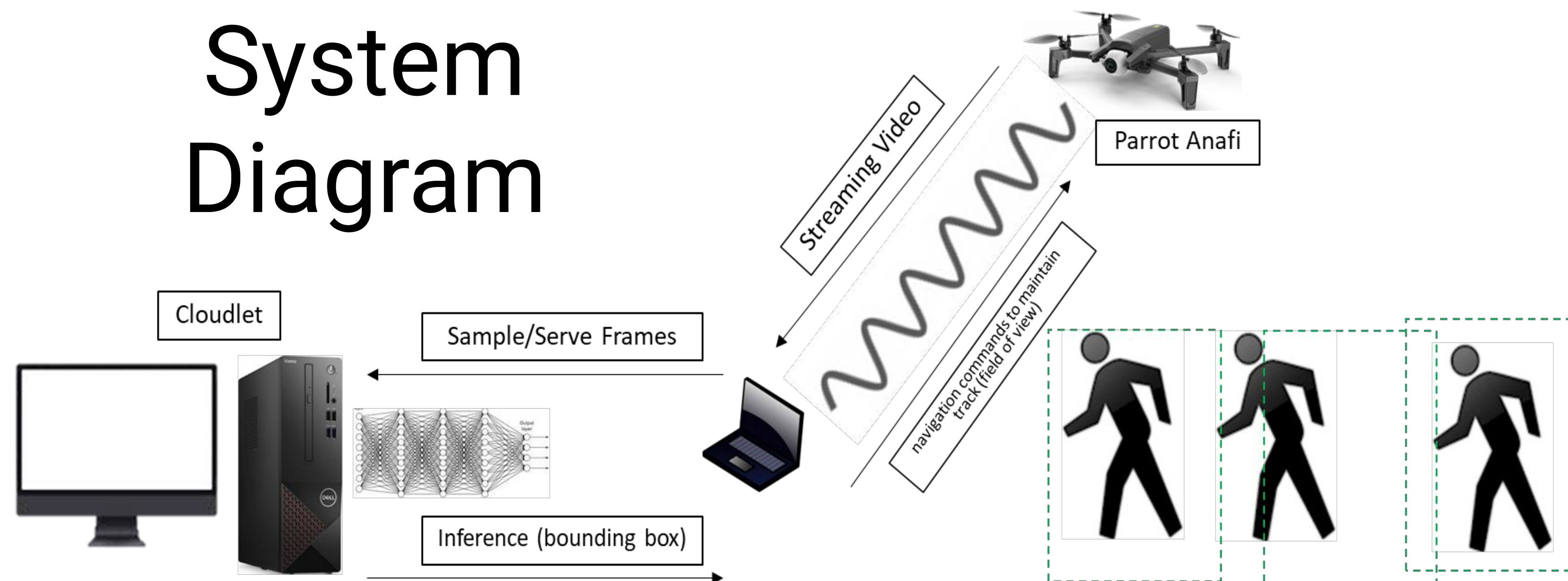


Tracking Objects with Edge-Enabled UAVs in High-Latency Environments

System Diagram



Drone Actuation

Yaw Determined By:

1. **Lateral position** of the center of the bounding box within the image (divided evenly into 5 parts)
2. **Prediction** of future location based on **history**
3. Current **distance** from the drone based on the height of the bounding box

Forward and Backward Motion Determined By:

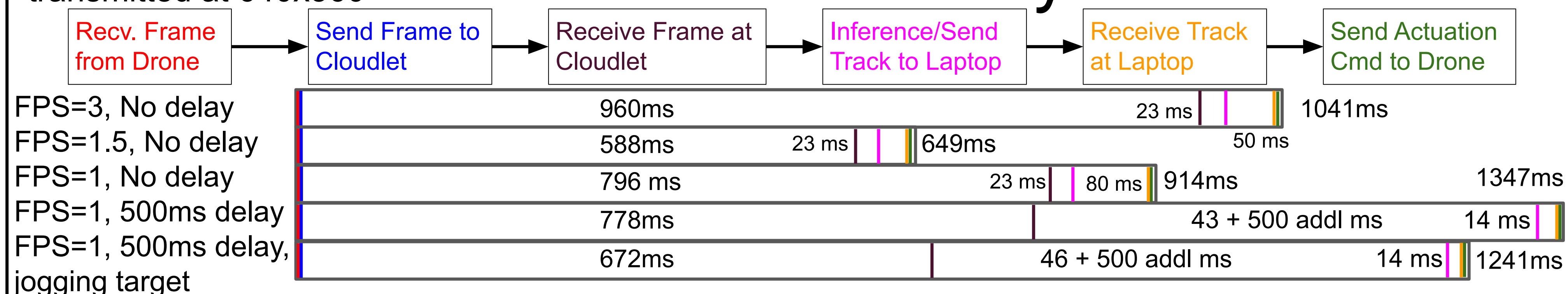
1. **Distance** from drone based on relative size of bounding box compared to image
2. **Prediction** of future location based on history
3. **Lateral position** of the bounding box



All images

transmitted at 640x360

Performance Analysis



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