

WIND MEASUREMENT BY MEANS OF A MULTICOPTER

The invention relates to a multicopter, using which wind measurements can be carried out, a method for wind measurement by means of a multicopter, and a
5 computer system, a digital storage medium, a computer program product, and a computer program.

The present invention relates to a multicopter, i.e., a free-flying drone or a free-flying robot driven by multiple propellers, which is used for wind measurement.
10 Multicopters are known in the prior art which are configured for wind measurement. Thus, a multicopter is disclosed in the publication: "Simultaneous Estimation of Aerodynamic and Contact Forces in Flying Robots: Application to Metric Wind Estimations and Collision Detection", ICRA 2015, Seattle, WA USA May 2015, pages: 5290-5296 of the present inventors: Tomic T. and Haddadin
15 S., which, on the basis of an estimation of a force screw τ_e acting externally on the multicopter, enables the estimation of a wind speed. The disclosure of this article, in particular the chapters: "III Modeling" and "IV Incorporating Aerodynamics into external Wrench Estimation" is hereby explicitly incorporated into the content of the disclosure of this description.

20 A controller of a multicopter is disclosed in the article "Aerodynamic Power Control for Multirotor Aerial Vehicles" by Bangura M. et al., in: IEEE International Conference on Robotics and Automation (ICRA), 31.05.-07.06.2014 Hong Kong, China, which has robust behavior in relation to wind disturbance and ground
25 effects.

A method is known from US 8,219,267 B2, using which the wind speed can be estimated during the operation of a UAV.

30 The object of the present invention is to specify a multicopter and a method for operating multicopter, using which an improved wind measurement is possible.

The invention results from the features of the independent claims. Advantageous refinements and embodiments of the subject matter of the dependent claims.
35 Further features, possible applications, and advantages of the invention result from the following description, and also the explanation of exemplary

embodiments of the invention which are illustrated in the figures.

One aspect of the invention relates to a multicopter having: a number N of electric motors MOT_n for driving N propellers $PROP_n$, where $n = 1, 2, \dots, N$ and $N \geq 2$, a first interface for providing first parameters P1 comprising: a 3D position $r_B = (x_b, y_b, z_b)$ of the center of gravity B of the multicopter, the time derivatives: $\dot{r}_B$ and $\ddot{r}_B$, a 3D orientation $o_M = (\alpha_M, \beta_M, \gamma_M)$ of the multicopter and its time derivative $\dot{o}_M$, a second interface for providing an aerodynamic power $P_{a,n}$ currently generated by the respective propellers $PROP_n$, a unit 803, which, on the basis of the first parameters P1 and/or the aerodynamic power $P_{a,n}$ and/or an estimation of one or more force screws τ_e externally acting on the multicopter, determines a relative speed $v_r := (v_{r,x}, v_{r,y}, v_{r,z})^T$ of the multicopter in relation to the air, a unit 805, which, on the basis of the determined relative speed $v_r := (v_{r,x}, v_{r,y}, v_{r,z})^T$ and on the basis of the parameter P1, determines the wind speed v_w in an inertial system, and a storage unit for storing the wind speeds $v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ determined for the locations r_B , and/or a transmission unit for the wireless transmission of the wind speed $v_w(r_B)$ to a receiver.

The determination of the relative speed $v_r := (v_{r,x}, v_{r,y}, v_{r,z})^T$ of the multicopter in relation to the air is advantageously performed by means of methods of neuronal learning and/or autonomous robot learning.

The arrangements of the propeller planes on the multicopter are fundamentally arbitrary in this case. The determination of the relative speed $v_r := (v_{r,x}, v_{r,y}, v_{r,z})^T$ therefore includes combinations of the estimated force screw and the estimated power.

If the propeller planes are arranged essentially parallel and in particular in one plane, the following special case thus results.

A further aspect of the invention relates to a multicopter having: a number N of electric motors MOT_n for driving N propellers $PROP_n$, where $n = 1, 2, \dots, N$ and $N \geq 2$, a first interface for providing first parameters P1 comprising: a 3D position $r_B = (x_b, y_b, z_b)$ of the center of gravity B of the multicopter (or providing items of

information from which the position $r_B = (x_b, y_b, z_b)$ of the center of gravity B of the multicopter can be determined/estimated), the time derivatives: $\dot{r}_B$ and $\ddot{r}_B$, a 3D orientation $o_M = (\alpha_M, \beta_M, \gamma_M)$ of the multicopter and its time derivative $\dot{o}_M$ (the variables $\dot{r}_B$, $\ddot{r}_B$, $o_M = (\alpha_M, \beta_M, \gamma_M)$, $\dot{o}_M$ are advantageously measured (for example, by means of GPS, LIDAR, cameras, etc., one or more inertial measuring units (IMU)) etc., observed, or derived (for example, by visual odometry, sensor data fusion such as Kalman filters etc.)), a second interface for providing an aerodynamic power $P_{a,n}$ currently generated by the respective propellers $PROP_n$ (which is advantageously measured or observed), a first unit, which, on the basis of the first parameters P1, on the basis of a provided model M1 for describing dynamics of the multicopter, and an estimation determined on the basis of the model M1 of a force screw τ_e acting externally on the multicopter, determines horizontal components $(v_{r,x}, v_{r,y})$ of a relative speed $v_r := (v_{r,x}, v_{r,y}, v_{r,z})^T$ of the multicopter in relation to the air (for this purpose function approximators are advantageously used, which are known from the field of “machine learning”, for example, linear regression, neuronal networks, multilayer perceptrons, support vector machines (SVM) etc.), a second unit which, on the basis of the determined horizontal components $(v_{r,x}, v_{r,y})$, and on the basis of the aerodynamic power $P_{a,n}$, determines the vertical component $(v_{r,z})$ of the relative speed v_r , a unit, which, on the basis of the determined horizontal components $(v_{r,x}, v_{r,y})$, the vertical component $(v_{r,z})$, and also on the basis of the parameters P1, determines the wind speed v_w , in an inertial system, a storage unit for storing the wind speeds $v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ determined for the locations r_B and/or a transmission unit for wirelessly transmitting the wind speed $v_w(r_B)$ to a receiver.

In the present case, the term “multicopter” describes an aircraft which has two or more drive units, in particular motor-driven propellers. The multicopter can also have lift and/or control surfaces. The arrangement of the N propellers $PROP_n$ on the multicopter is arbitrary in principle. Each propeller is advantageously described in its own coordinate system. The N propellers $PROP_n$ can advantageously be vectored, i.e., each propeller can be described in its own time-variable coordinate system. The method can accordingly be generalized in

principle to other arrangements, in which the arrangement of the propellers is not necessarily in one plane. The corresponding required combinations of the estimators is derivable in an obvious manner from the described common case.

- 5 In principle, the proposed method can in other words execute a regression from the external force screw τ_e to the relative speed v_r , a regression from the aerodynamic powers $P_{a,n}$ to the relative speed v_r , and/or a regression from the external force screw τ_e and the aerodynamic powers $P_{a,n}$ to the relative speed v_r .
- 10 The relationship: $v_r = \dot{r}_B - v_w$ advantageously applies in this case, where:
 $v_r := (v_{r,x}, v_{r,y}, v_{r,z})^T$:= relative speed of the multicopter in relation to the air, and
 $v_w := (v_{w,x}, v_{w,y}, v_{w,z})^T$ is the wind speed.

The proposed multicopter thus solely uses the approach disclosed in the article
 15 indicated at the outset to determine the horizontal components $(v_{r,x}, v_{r,y})$ of the relative speed v_r , in which, based on a model of the dynamics of the multicopter and an estimation generated thereby of a force screw τ_e acting externally on the multicopter, an estimation of the relative speed v_r is performed.

- 20 The determination of the vertical component $(v_{r,z})$ of the relative speed v_r is performed in the present case on the basis of the determination of the aerodynamic power of the respective motor-propeller combinations and also on the basis of the previously determined horizontal components $(v_{r,x}, v_{r,y})$ of the relative speed v_r . The proposed multicopter thus enables a more accurate and
 25 robust determination of wind speeds during flight. It can therefore be used in particular as a flying wind sensor, which stores the determined wind data on board and/or transmits them to a ground station.

Several relationships and mathematical principles are described hereafter, which
 30 are used for the explanation and the implementation of the invention.

I. Movement equations (rigid-body mechanics)

The movement equations applicable to the present multicopter can fundamentally
 35 be formulated as follows:

(Eq. 1) $m\ddot{r} = mge_3 + Rf + Rf_e$

(Eq. 2) $I\dot{\omega} = (I\omega) \times \omega - mg(r_g) \times R^T e_3 + \overline{m} + \overline{m}_e$

(Eq. 3) $\dot{R} = R(\omega) \times$

5 where:

m : mass of the multicopter

$r_B = (x, y, z)^T$: position of the multicopter in a fixed north-east-bottom inertial system

$R \in SO(3)$: rotation matrix from a multicopter reference system to the inertial system

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$I \in \Re^{3 \times 3}$: moment of inertia of the multicopter

$(\cdot) \times$: skew symmetric matrix operator

g : acceleration of gravity

ω : angular speed of the multicopter

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e_3 : unity vector of the z axis in the inertial system

r_g : position of the mass center of gravity of the multicopter in the multicopter reference system

f : target force in the multicopter reference system

f_e : external force acting on the multicopter in the multicopter reference system

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$\overline{m}$: target torque in the multicopter reference system

$\overline{m}_e$: effective torque acting externally on the multicopter in the multicopter reference system.

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In this case, there are the target force screw $\tau = [f^T, \overline{m}^T]^T$ generated by the propeller electric motor units and the force screw $\tau_e = [f_e^T, \overline{m}_e^T]^T$ acting externally on the multicopter. In general, $\tau = [f^T, \overline{m}^T]^T$ is dependent on the free flow speed v_∞ and the propeller speed ϖ . The term “free flow speed” v_∞ is understood in the present case as the speed of an airflow which is uninfluenced by the multicopter.

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II. Estimation of the external force screw

The estimation of the force screw $\tau_e = [f_e^T, \overline{m}_e^T]^T$ acting externally on the multicopter is advantageously performed on the basis of the following relationships:

$$(Eq. 4) \quad \hat{\tau}_e = \begin{bmatrix} \int_0^t K_I^f (ma - f - \hat{f}_e) dt \\ K_I^m (I\omega - \int_0^t (m + (I\omega) \times \omega - mg(r_g) \times R^T e_3 + \overline{m}_e) dt) \end{bmatrix}$$

where:

K_I^f and K_I^m : amplification factors of filters

$a = R^T(\ddot{r} - ge_3)$: acceleration measured in the reference system of the multicopter

10 $\hat{f}_e$ and $\overline{\hat{m}}_e$: estimated external force or external torque, respectively, acting on the multicopter.

More detailed statements in this regard result, for example, from the article by Tomic T., "Evaluation of acceleration-based disturbance observation for multicopter control" in European Control Conference (ECC), 2014, pages 2937-2944.

III. Propeller aerodynamics

20 The forces acting on a propeller of the multicopter are dependent on the free flow speed v_∞ (relative wind speed). The free flow speed v_∞ of the n -th propeller in a reference system of the propeller can be expressed as follows:

$$(Eq. 5) \quad v_\infty^{(n)} = R_{pb}^{(n)} (R_{bi}^{(n)} v_r + \omega \times r_n)$$

25

Wherein $v_r = \dot{r}_B - v_w$ is the true airspeed of the multicopter, v_w is the wind speed, $R_{bi}^{(n)}$ is the rotation matrix from the inertial system to the reference system of the multicopter, $R_{pb}^{(n)}$ is the rotation matrix from the reference system of the multicopter to the reference system of the propeller, ω is the angular speed of the multicopter, and r_n is the position of the respective propeller in relation to the reference system of the multicopter. On the basis of preservation of momentum, the following results for the thrust T generated by the n -th propeller

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(Eq. 6) $T = 2\rho A v_i U$

where: ρ := air density, A := area swept by the propeller, and $U = \|v_i e_3 + v_\infty\|$ is the total wake flow generated by the propeller. The flow speed v_i induced by the propeller can advantageously be determined as follows:

(Eq. 7) $v_i = v_h^2 / \sqrt{v_{xy}^2 + (v_i - v_z)^2}$

The solution is advantageously performed by means of a Newton-Raphson method in a few steps with known v_h and v_∞ . For the horizontal and the vertical component of the free flow speed, the following applies: $v_{xy} = v_\infty - v_z$ and $v_z = e_3^T v_\infty$. In hovering flight, the following applies for the induced speed: $v_i = v_h = \sqrt{T_h / 2\rho A}$, wherein the hovering flight thrust T_h results from $T_h = \rho D^4 C_T \omega^2$. The thrust coefficient C_T is advantageously determined from static thrust measurements. D indicates the diameter of the respective propeller and ω indicates the propeller rotational speed. The ideal aerodynamic propeller power is given by:

(Eq. 8) $P_a = 2\rho A v_i U (v_i - v_z)$

The aerodynamic power in forward flight in relation to the hovering flight power is:

(Eq. 9) $P_a / P_h = (v_i - v_z) / v_h$

given by $P_h = 2\rho A v_h^3$. Deviations from the ideal behavior can be taken into consideration by introducing a factor FM between 0 and 1. The relationship between aerodynamic power P_a of a drive unit (electric motor and propeller) and the motor power P_M generated by an electric motor results in this case as:

$P_a = P_M \cdot \text{FM}$.

IV. Model for describing a brushless DC electric motor

The following dynamic motor model is advantageously used to estimate the aerodynamic power of a drive unit.

$$(Eq. 10) \quad \tau_m = (K_{q0} - K_{q1}i_a)i_a$$

$$(Eq. 11) \quad I_r \dot{\omega}_E = \tau_m - D_r$$

where: i_a := motor current, ω_E := angular speed of the electric motor, τ_m :=
 5 torque of the electric motor, wherein the torque factor $K_q(i_a)$ is advantageously
 modeled as follows: $K_q(i_a) = (K_{q0} - K_{q1}i_a)$ with the constants: K_{q0} , K_{q1} . I_r is the
 moment of inertia of the electric motor and D_r is the aerodynamic moment of
 friction which acts on the motor. The total mechanical power output by the electric
 motor results as: $P_m = P_a/FM + P_r$, where P_m := mechanical power of the electric
 10 motor and P_r := power which is required to accelerate the electric motor rotor, is
 advantageously used to determine an estimation of the aerodynamic power P_a as
 follows:

$$(Eq. 12) \quad P_m = \tau_m \omega_E = (K_{q0} - K_{q1}i_a)i_a \omega_E$$

$$15 \quad (Eq. 13) \quad P_r = I_r \omega_E \dot{\omega}_E$$

$$(Eq. 14) \quad P_a = FM((K_{q0} - K_{q1}i_a)i_a - I_r \dot{\omega}_E) \omega_E$$

In summary, this means that the motor current i_a is measured or estimated. The
 variables ω_E and $\dot{\omega}_E$ can also be measured or estimated in dependence on i_a .

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V. Estimation of the wind speed v_w based on the determination of an external
 force screw τ_e

As stated in the article mentioned at the outset, the wind speed can be
 25 determined based on the force screw τ_e acting externally on the multicopter. It is
 assumed in this case that the force screw τ_e may be attributed exclusively to
 aerodynamic τ_d friction forces: $\tau_e = \tau_d$, so that the fundamental aerodynamic
 model M1 merely has to be inverted: $\tau_d = d(v_r)$. For simple aerodynamic
 models, this can be performed via a simple relation or iteration. If one uses, for
 30 example, a linear model M1 as a basis, the following thus applies, for example:

$$(Eq. 15) \quad d(v_r) = D_l v_r \sum \omega^{(n)}$$

where D_l := linear coefficient matrix. If $\hat{f}_e = d(v_r)$ is used, the following results:

$$(Eq. 16) \quad v_r(d) = \frac{1}{\sum \varpi_i} D \hat{f}_e$$

where: $D :=$ a coefficient matrix. This simple model furthermore implies that the
5 multicopter has a symmetrical shape.

Alternatively, a learning-based approach can be followed. The above relation can
also be modeled by means of a radial basis function (RBF) neuronal network.
This has the advantage that the inverse relation is coded directly in the radial
10 basis function. The relation $v_r = d^{-1}(\tau_e)$ is advantageously modeled as a
normalized RBF network having K base functions:

$$(Eq. 17) \quad v_r = \frac{1}{\varphi_\Sigma} W \varphi(\tau_e)$$

15 where: $W \in \mathbb{R}^{3 \times K} :=$ matrix having weighting constants of the RBFs for each
speed component:

$$(Eq. 18) \quad W = \begin{bmatrix} w_x^T \\ w_y^T \\ w_z^T \end{bmatrix} = \begin{bmatrix} w_{x,1} & \cdots & w_{x,K} \\ w_{y,1} & \cdots & w_{y,K} \\ w_{z,1} & \cdots & w_{z,K} \end{bmatrix}$$

20 and where: $\varphi = [\varphi(r_1), \dots, \varphi(r_K)]^T$ of the evaluated base functions. The network is
advantageously normalized by the factor: $\varphi_\Sigma = \sum_{i=1}^K \varphi(r_i)$. Gaussian base
functions are advantageously used:

$$(Eq. 19) \quad \varphi(r_i) = \exp\left(-\frac{1}{\sigma^2} \|x - c_i\|^2\right)$$

25 where $\sigma :=$ form parameter, $x :=$ the determined vector, and $c_i :=$ the center of
the i -th base function.

VI. Wind measurements on the basis of determined aerodynamic powers of
30 the drive units each consisting of propeller and electric motor

Proceeding from the equations (Eq. 7), (Eq. 8), and (Eq. 9), the aerodynamics for
a propeller can be formulated as a system of nonlinear equations

$F(v_{r,z}, v_{r,xy}, v_i, v_h, P_a) = 0$ and $F = [F_1, F_2, F_3]^T$, where:

$$(Eq. 21) \quad F_1 = v_i^4 - 2v_i^3 v_{r,z} + v_i^2(v_{r,xy}^2 + v_{r,z}^2) - v_h^4 = 0$$

$$F_2 = v_i U(v_i - v_{r,z}) - P_a / (2\rho A_n) = 0$$

$$5 \quad F_3 = v_h^2(v_i - v_{r,z}) - P_a / (2\rho A_n) = 0$$

It is presumed that $P_a / (2\rho A)$ and v_h are known and the vector $x = (v_{r,x}, v_{r,y}, v_{r,z}, v_i)^T$ is to be determined. The above-mentioned system of nonlinear equations (Eq. 21) is under-determined, since three unknown and only
 10 two known variables are present (in this case, the horizontal components $v_{r,x}$ and $v_{r,y}$ are coupled in $v_{r,xy}$. A plurality of solutions of the equation system (Eq. 21) thus results. To solve this minimization problem, it is proposed that the system of the equations (Eq. 21) be expanded in such a way that a plurality (number K) of “measurements” of P_a is integrated into the equation system.

15

Overall, K measurements are thus carried out to determine the aerodynamic power $P_{a,n}$. The aerodynamic power $P_{a,n}$ can be produced in this case, for example, K times for a single electric motor and its propeller. Advantageously, the K “measurements” of the aerodynamic power $P_{a,n}$ are performed for two or
 20 more different electric motors and the propellers thereof. Finally, for the K different measurements, a transformation of the equation system (Eq. 21) into a common reference system is performed. This fundamentally enables the estimation of all three components of the relative wind direction and the wind speed v_i induced by the propeller by solving the nonlinear quadratic minimization
 25 problem (Eq. 21).

25

It is presumed in this case that during the K “measurements” of the aerodynamic power P_a , the wind speed $v_w = [v_{w,x}, v_{w,y}, v_{w,z}]$ remains equal. If the K measurements are carried out in a sufficiently short time, this assumption is thus
 30 adequately justified. Sufficiently accurate wind measurements require K determinations of the aerodynamic power, wherein it is sufficient to select K advantageously ≤ 10 , or K advantageously in the range of 3 to 8. The higher K is selected, the greater is the computing effort and accompanying this also the period of time in which measurements are carried out, so that as a period of time

becomes longer, the probability of a variation of the wind in the period of time rises.

Advantageously, N measurements or determinations of the aerodynamic power P_a are carried out simultaneously on the K electric motor propeller units. If, for example, $K = 8$ is selected and the multicopter has four drive units, only two successive “measurements” of the aerodynamic power P_a are thus required per drive unit. “Measurements” of the aerodynamic power P_a from a variety of poses of the multicopter at different points in time in a small time window can advantageously be combined. If the flight of the multicopter is not aggressive, i.e., the orientation of the multicopter does not change significantly in the measuring period of time, the free flow speed v_∞ in the reference system of the multicopter can thus be estimated sufficiently accurately. Overall, K “measurements” of the aerodynamic power P_a are thus carried out to determine the vertical component $[v_{w,z}]$ of the wind direction v_w .

The state vector x to be determined for K measurements is:

$$(Eq. 22) \quad x = [v_{r,x}, v_{r,y}, v_{r,z}, v_{i,1}, v_{i,2}, \dots, v_{i,K}]^T$$

wherein the expanded equation system has to be solved:

$$(Eq. 23) \quad F(v_{r,x}, v_{r,y}, v_{r,z}, v_{i,1}, v_{i,2}, \dots, v_{i,K}, P_{a,1}, \dots, P_{a,K}) = 0$$

$$F = [F_{1,1}, F_{2,1}, F_{3,1}, \dots, F_{1,K}, F_{2,K}, F_{3,K}]^T$$

Wherein $F_{1,k}, F_{2,k}, F_{3,k}$ are evaluations of the equation system (Eq. 21) for the k -th “measurement” of the aerodynamic powers. To solve the equation (Eq. 23), a Jacobi matrix is required. The Jacobi matrix for the k -th measurement results as:

$$(Eq. 24) \quad \mathfrak{J}^{(k)} = \begin{bmatrix} J_{11}^{(k)} & J_{12}^{(k)} & J_{13}^{(k)} & J_{14}^{(k)} \\ J_{21}^{(k)} & J_{22}^{(k)} & J_{23}^{(k)} & J_{24}^{(k)} \\ J_{31}^{(k)} & J_{32}^{(k)} & J_{33}^{(k)} & J_{34}^{(k)} \end{bmatrix}$$

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where: $J_{ij}^{(k)} = \partial F_{i,k} / \partial x_{j,k}$. The expanded Jacobi matrix $\mathfrak{J} \in \mathbb{R}^{3K \times K+3}$ can thus now be constructed. In the exemplary case of three measurements ($K = 3$), the following results: $x|_{N=3} = [v_{r,x}, v_{r,y}, v_{r,z}, v_{i,1}, v_{i,2}, v_{i,3}]^T$ and

$$\mathfrak{J}|_{N=3} = \begin{bmatrix} J_{11}^{(1)} & J_{12}^{(1)} & J_{13}^{(1)} & J_{14}^{(1)} & 0 & 0 \\ J_{21}^{(1)} & J_{22}^{(1)} & J_{23}^{(1)} & J_{24}^{(1)} & 0 & 0 \\ J_{31}^{(1)} & J_{32}^{(1)} & J_{33}^{(1)} & J_{34}^{(1)} & 0 & 0 \\ J_{11}^{(2)} & J_{12}^{(2)} & J_{13}^{(2)} & 0 & J_{14}^{(2)} & 0 \\ J_{21}^{(2)} & J_{22}^{(2)} & J_{23}^{(2)} & 0 & J_{24}^{(2)} & 0 \\ J_{31}^{(2)} & J_{32}^{(2)} & J_{33}^{(2)} & 0 & J_{34}^{(2)} & 0 \\ J_{11}^{(3)} & J_{12}^{(3)} & J_{13}^{(3)} & 0 & 0 & J_{14}^{(3)} \\ J_{21}^{(3)} & J_{22}^{(3)} & J_{23}^{(3)} & 0 & 0 & J_{24}^{(3)} \\ J_{31}^{(3)} & J_{32}^{(3)} & J_{33}^{(3)} & 0 & 0 & J_{34}^{(3)} \end{bmatrix}.$$

An expansion to K measurements is easily possible for a person skilled in the art.

- 5 If measurements from various poses of the multicopter are combined, the wind speeds resulting in each case have to be transformed into a common reference system.

The free flow speed for the n -th propeller is advantageously defined as follows:

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$$(Eq. 25) \quad v_{\infty}^{(n)} = \begin{bmatrix} v_{\infty,x}^{(n)} \\ v_{\infty,y}^{(n)} \\ v_{\infty,z}^{(n)} \end{bmatrix} = R^{(n)} \begin{bmatrix} v_{\infty,x} \\ v_{\infty,y} \\ v_{\infty,z} \end{bmatrix} + v_0^{(n)}$$

- Wherein the transformed speeds are used to compute equations (Eq. 21) and (Eq. 24). The offset speed $v_0^{(n)}$ can be obtained from a pose estimation system
- 15 as the difference speed between two measurements. The offset speed of the propeller on the basis of an angular speed of the multicopter can advantageously also be used, for example, $v_0^{(n)} = R_{pb}^{(n)} \omega \times r_n$. The rotation matrix $R^{(n)}$ transforms the relative speed from the common coordinate system into the propeller coordinate system. This formulation advantageously enables the independent
 - 20 determination of all three components of the free flow speed. Furthermore, it also permits the determination of the wind components v_w for the case in which the propellers are not arranged in a coplanar configuration on the multicopter.

If the equations “match”, a multidimensional optimization problem is to be solved.

- 25 The solution is then in the intersection of all nonlinear functions for which the

following applies: $F = 0$. In the general case, however, an intersection does not result for all nonlinear functions. In this case, a nonlinear quadratic minimization problem has to be solved using the following objective function:

5 (Eq. 26) $\bar{f} = \frac{1}{2} F^T F.$

This is advantageously performed using a Levenberg-Marquard method. If an exact solution exists, $\bar{f} = 0$ applies, i.e., the intersection of $F = 0$. In all other cases, a quadratic minimized solution results.

10

The solution space of the equation (Eq. 26) contains local optima. Based on the fundamental physics, the same measured aerodynamic powers P_a can occur at different wind speeds v_w and induced speeds v_i . The optimized variables are speeds. It is therefore advisable to use physical considerations as the foundation, to differentiate reasonable solutions from nonsensical solutions. A multicopter has to use power to generate thrust, which means $T > 0$ and $P_a > 0$. The induced speed v_i is less than the hovering flight speed v_h . The induced speed is advantageously restricted to a range $0 < v_i < v_h$.

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One advantageous refinement of the multicopter is distinguished in that the second unit is embodied and configured for the purpose of solving the following quadratic minimization problem or one which is transferable thereto or is equivalent in its basic concepts for a number of a total of K measurements of the aerodynamic power $P_{a,n}$ for f , where $k = 1, \dots, K$ and $K \geq 1$:

25

(1) $\bar{f} = \frac{1}{2} F^T F$

wherein the following applies:

(2) $F(v_{r,x}, v_{r,y}, v_{r,z}, v_{i,1}, v_{h,1}, P_{a,1}, \dots, v_{i,K}, v_{h,K}, P_{a,K}) = 0,$

(3) $F = [F_{1,1}, F_{2,1}, F_{3,1}, \dots, F_{1,K}, F_{2,K}, F_{3,K}],$

(4) $F_{1,k} = v_{i,k}^4 - 2v_{i,k}^3 v_{r,z} + v_{i,k}^2 (v_{r,x}^2 + v_{r,y}^2 + v_{r,z}^2) - v_{h,k}^4 = 0$

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(5) $F_{2,k} = v_{i,k} U_k (v_{i,k} - v_{r,z}) - P_{a,k} / (2\rho A_n) = 0$

(6) $F_{3,k} = v_{h,k}^2 (v_{i,k} - v_{r,z}) - P_{a,k} / (2\rho A_n) = 0$

(7) $U_k = \sqrt{v_{r,x}^2 + v_{r,y}^2 + (v_{i,k} - v_{r,z})^2}$

where

- A_n : area swept by the n -th propeller,
 ρ : air density,
 $v_{h,k}(P_{a,n,k})$: induced speed of the n -th propeller in hovering flight for the k -th measurement,
5 $v_{i,k}(P_{a,n,k})$: speed induced by the n -th propeller for the k -th measurement.

Above equations (1) to (7) are described in the respective propeller coordinate system.

- 10 One advantageous refinement of the multicopter is distinguished in that the second unit is embodied and configured in such a way that the horizontal components ($v_{r,x}, v_{r,y}$) of the relative speed v_r determined by the first unit are taken into consideration in the nonlinear quadratic minimization problem by the following relationships or relationships transferable thereto:

15 (9) $F_{4,k} = v_{r,x,k} - v_{r,x} = 0$

(10) $F_{5,k} = v_{r,y,k} - v_{r,y} = 0$

- The equations (9) and (10) are described in the respective propeller coordinate system. Therefore, the speed estimated according to present claim 1 can be
20 projected in the propeller coordinate system, so that these equations apply.

An advantageous refinement of the multicopter is distinguished in that the model M1 is based on the following movement equation or the model M1 can be traced back to the following movement equation:

25

$$M\dot{v} + C(v)v + g_M = J^T \tau + \tau_e$$

wherein the following applies: $\tau_e = \tau_d(v_r)$ and $v_r = \dot{r}_B - v_w$

M : generalized mass of the multicopter

v : generalized speed $[\dot{r}_b^T, \omega^T]$

- 30 ω : angular speed of the multicopter

$\dot{v}$: time derivative of v

$$C(v) = \begin{bmatrix} 0_{3 \times 3} & 0_{3 \times 3} \\ 0_{3 \times 3} & -(I\omega) \times \end{bmatrix}$$

g_M : weight of the multicopter

J : block diagonals of the Jakobi matrix
 τ : target force screw $[f^T, \overline{m}^T]$ to be generated by the electric motors MOT_n
 τ_e : force screw $[f_e^T, \overline{m}_e^T]$ acting externally on the multicopter
5 $\tau_d(v_r)$: external force screw generated exclusively by air friction
 v_r : $= (v_{r,x}, v_{r,y}, v_{r,z})^T$ relative speed of the multicopter in relation to the air
 v_w : $= (v_{w,x}, v_{w,y}, v_{w,z})^T$ wind speed.

- 10 One advantageous refinement of the multicopter is distinguished in that a control system is provided for controlling and regulating the electric motors MOT_n , wherein the control system is embodied and configured in such a way that the electric motors MOT_n are regulated in such a way that the projection of the determined wind speed v_w on the direction of axis of rotation of the propellers
- 15 $PROP_n$ is maximized.

The fundamental optimization problem can also be mathematically formulated. For this purpose, an orientation o^* has to be determined which minimizes the condition number of the Jakobi matrix, by $o^* = \text{argmin } K(J)$, wherein K is the

20 condition number.

Trajectory planning can advantageously be used for this purpose in particular and/or the control of the multicopter can be adapted to the optimal wind estimation. The solution can also be generated by gradient methods, potential-

25 based methods, or other equivalent mathematical solutions.

The accuracy of the wind measurement is enhanced and the robustness of the measurement is improved by this measure.

- 30 A 3D acceleration sensor and a gyroscope and also a position determination system are advantageously provided in the multicopter and are connected to the first interface for determining the first parameters $P1$. The position determination system is advantageously a satellite navigation system and/or an optical navigation system.

35

One advantageous refinement of the multicopter is distinguished in that for the determination of the aerodynamic power $P_{a,n}$ per electric motor MOT_n , a motor current sensor, a motor rotational speed sensor, or a motor rotational speed estimator are provided, and also a unit which determines the aerodynamic power

5 $P_{a,n}$ on the basis of a predetermined model M2 for describing the propeller dynamic range, the detected motor currents, and motor rotational speeds. At least one corresponding model M2 was already explained above.

A further aspect of the invention relates to methods for measuring a wind speed

10 v_w using a multicopter, wherein the multicopter has a number N of electric motors MOT_n for driving N propellers $PROP_n$, where $n = 1, 2, \dots, N$ and $N \geq 2$, comprising the following steps: providing first parameters P1 comprising: a 3D position $r_B = (x_b, y_b, z_b)$ of the center of gravity B of the multicopter, the time derivatives: $\dot{r}_B$ and $\ddot{r}_B$, a 3D orientation $o_M = (\alpha_M, \beta_M, \gamma_M)$ of the multicopter and its time

15 derivative $\dot{o}_M$, providing an aerodynamic power $P_{a,n}$ currently generated by the respective propellers $PROP_n$ on the basis of the first parameters P1 and/or the aerodynamic power $P_{a,n}$ and/or an estimation of one or more force screws τ_e acting externally on the multicopter, determining a relative speed $v_r := (v_{r,x}, v_{r,y}, v_{r,z})^T$ of the multicopter in relation to the air on the basis of the

20 determined relative speed $v_r := (v_{r,x}, v_{r,y}, v_{r,z})^T$ and on the basis of the parameters P1, determining the wind speed v_w in an inertial system, and storing the wind speeds $v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ determined for the locations r_B , and/or transmitting the wind speed $v_w(r_B)$ to a receiver.

25 A further aspect of the present invention relates to a method for measuring a wind speed v_w using a multicopter, wherein the multicopter has a number N of electric motors MOT_n for driving N propellers $PROP_n$, where $n = 1, 2, \dots, N$ and $N \geq 2$ comprising the following steps.

30 In one step, a provision of first time-dependent parameters P1 is performed, comprising a 3D position $r_B = (x_b, y_b, z_b)$ of the center of gravity B of the multicopter (or providing pieces of information from which the position $r_B = (x_b, y_b, z_b)$ of the center of gravity B of the multicopter can be

determined/estimated), the time derivatives: $\dot{r}_B$ and $\ddot{r}_B$, a 3D orientation $o_M = (\alpha_M, \beta_M, \gamma_M)$ of the multicopter and the time derivative $\dot{o}_M$ (the variables $\dot{r}_B$, $\ddot{r}_B$, $o_M = (\alpha_M, \beta_M, \gamma_M)$, $\dot{o}_M$ are advantageously measured (for example, by means of GPS, LIDAR, cameras, etc., one or more inertial measuring units (IMU)) etc.,
5 observed or derived (for example, by visual odometry, sensor data fusion such as Kalman filters etc.)). In a further step, a provision of an aerodynamic power $P_{a,n}$ generated by the respective propellers $PROP_n$ is performed (which is advantageously measured or observed). In a further step, on the basis of the first parameters P1 and/or a provided model M1 for describing dynamics of the
10 multicopter and/or an estimation determined on the basis of the model M1 of one or more force screws τ_e acting externally on the multicopter, a determination is performed of horizontal components $(v_{r,x}, v_{r,y})$ of a relative speed v_r of the multicopter in relation to the air (for this purpose functional approximators are advantageously used, which are known from the field of “machine learning”, for
15 example, linear regression, neuronal networks, multilayer perceptrons, deep neuronal networks, convolution networks, recurrent networks, for example, LSTM networks, support vector machines (SVM) etc.). In a further step, on the basis of the determined horizontal components $(v_{r,x}, v_{r,y})$ and the aerodynamic power $P_{a,n}$, a determination is performed of the vertical component $(v_{r,z})$ of the relative
20 speed v_r . In a further step, on the basis of the determined relative speed $v_r = (v_{r,x}, v_{r,y}, v_{r,z})$ and on the basis of the parameters P1, a determination is performed of the wind speed v_w in an inertial system. Finally, storage is performed of the wind speed determined for
 $r_B: v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ and/or transmission of the wind speed:
25 $v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ to a receiver.

The horizontal components $(v_{r,x}, v_{r,y})$ are thus determined by measuring the force screw acting externally on the multicopter using the equations (Eq. 16) and (Eq. 17). Based on the determined horizontal components $(v_{r,x}, v_{r,y})$ and a determined
30 aerodynamic power P_a , the vertical component $(v_{r,z})$ is determined.

Finally, the three-dimensional wind speed can be determined, stored, transmitted, and possibly subsequently output by way of the relationship $v_r = \dot{r}_B - v_w$.

One advantageous refinement of the proposed method is distinguished in that the following nonlinear quadratic minimization problem or one transferable thereto is solved for a number of a total of K measurements of the aerodynamic power $P_{a,n}$

5 for f , where $k = 1, 2, \dots, K$ and $K \geq 1$:

$$(1) \quad \bar{f} = \frac{1}{2} F^T F$$

wherein the following applies:

$$(2) \quad F(v_{r,x}, v_{r,y}, v_{r,z}, v_{i,1}, v_{h,1}, P_{a,1}, \dots, v_{i,K}, v_{h,K}, P_{a,K}) = 0,$$

$$(3) \quad F = [F_{1,1}, F_{2,1}, F_{3,1}, \dots, F_{1,K}, F_{2,K}, F_{3,K}],$$

$$10 \quad (4) \quad F_{1,k} = v_{i,k}^4 - 2v_{i,k}^3 v_{r,z} + v_{i,k}^2 (v_{r,x}^2 + v_{r,y}^2 + v_{r,z}^2) - v_{h,k}^4 = 0,$$

$$(5) \quad F_{2,k} = v_{i,k} U_k (v_{i,k} - v_{r,z}) - P_{a,k} / (2\rho A_n) = 0$$

$$(6) \quad F_{3,k} = v_{h,k}^2 (v_{i,k} - v_{r,z}) - P_{a,k} / (2\rho A_n) = 0$$

$$(7) \quad U_k = \sqrt{v_{r,x}^2 + v_{r,y}^2 + (v_{i,k} - v_{r,z})^2}$$

where

15 A_n : area swept by the n -th propeller,

ρ : air density

$v_{h,k}(P_{a,n,k})$: induced speed of the n -th propeller in hovering flight for the k -th measurement,

$v_{i,k}(P_{a,n,k})$: speed induced by the n -th propeller for the k -th measurement.

20

Above equations (1) to (7) are described in the respective propeller coordinate system.

One advantageous refinement of the proposed method is distinguished in that the determined horizontal components ($v_{r,x}, v_{r,y}$) are taken into consideration in the nonlinear quadratic minimization problem by the following relationships or relationships transferable thereto:

$$(9) \quad F_{4,k} = v_{r,x,k} - v_{r,x} = 0$$

$$(10) \quad F_{5,k} = v_{r,y,k} - v_{r,y} = 0$$

30

Equations (9) and (10) are described in the respective propeller coordinate system. Therefore, the speed estimated according to present claim 1 can be projected into the propeller coordinate system so that these equations apply.

One advantageous refinement of the proposed method is distinguished in that the model M1 is based on the following movement equation or the model M1 can be traced back to the following movement equation:

5

$$M\dot{v} + C(v)v + g_M = J^T \tau + \tau_e$$

wherein the following applies: $\tau_e = \tau_d(v_r)$ and $v_r = \dot{r}_B - v_w$

M : generalized mass of the multicopter

v : generalized speed $[r_b^T, \omega^T]$

10 ω : angular speed of the multicopter

$\dot{v}$: time derivative of v

$$C_v = \begin{bmatrix} 0_{3 \times 3} & 0_{3 \times 3} \\ 0_{3 \times 3} & -(I\omega) \times \end{bmatrix}$$

g_M : weight of the multicopter

J : block diagonals of Jakobi matrix

τ : target force screw $[f^T, \bar{m}^T]$ to be generated by the electric motors

15 MOT_n

τ_e : force screw $[f_e^T, \bar{m}_e^T]$ acting externally on the multicopter

$\tau_d(v_r)$: external force screw generated exclusively by air friction

v_r : $= (v_{r,x}, v_{r,y}, v_{r,z})^T$ relative speed of the multicopter in relation to the air

20 v_w : $= (v_{w,x}, v_{w,y}, v_{w,z})^T$ wind speed.

One advantageous refinement of the proposed method is distinguished in that a control system is provided for controlling and regulating the electric motors MOT_n , wherein the electric motors MOT_n are regulated in such a way that the projection
25 of the wind speed v_w on the direction of the axis of rotation of the propellers is maximized.

One advantageous refinement of the proposed method is distinguished in that for the determination of the aerodynamic power $P_{a,n}$ per electric motor MOT_n , a
30 motor current and a motor rotational speed are determined, and, on the basis of a predetermined model M2 for describing the propeller dynamic range, the

detected motor currents, and motor rotational speeds, the aerodynamic power $P_{a,n}$ is determined.

One advantageous refinement of the proposed method is distinguished in that the
5 determination of the horizontal components $(v_{r,x}, v_{r,y})$ is performed by means of a model of the aerodynamic force screw, which describes the dependence $v_r(\tau_e)$.

One advantageous refinement of the proposed method is distinguished in that the
10 nonlinear quadratic minimization problem is solved by means of a nonlinear optimization method (for example, Levenberg-Marquardt).

A further aspect of the invention relates to a computer system having a data
processing device, wherein the data processing device is designed in such a way
15 that a method as described above is executed on the data processing device.

A further aspect of the invention relates to a digital storage medium having
electronically readable control signals, wherein the control signals can interact
with a programmable computer system so that a method as described above is
20 executed.

A further aspect of the invention relates to a computer program product having
program code stored on a machine-readable carrier for carrying out the method
as described above with the program code is executed on a data processing
25 device.

A further aspect of the invention relates to a computer program having program
code for carrying out the method as described above when the program runs on
a data processing device. For this purpose, the data processing device can be
designed as an arbitrary computer system known from the prior art.

A further aspect of the invention relates to a system comprising two or more
30 multicopters as described above, wherein the multicopters are each also embodied and configured for bilateral data exchange with one another in a data network and the multicopters transmit the respective determined wind speed:
35 $v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ to the respective other multicopter. The data exchange preferably takes place via radio and/or optical data transmission.

The multicopters are advantageously embodied as agents or softbots for wireless communication in the data network. The term “agent” is used in the present case in the following meaning: “computer system which is located in a specific environment and is capable of carrying out independent actions in this environment to achieve its (predetermined) goals”.

One advantageous refinement of the proposed method is distinguished in that the control system for controlling and regulating the electric motors MOT_n of the respective multicopter is embodied and configured in such a way that determined wind speeds transmitted from the other multicopters: $v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ are taken into consideration in the regulation and movement planning.

One advantageous refinement of the proposed method is distinguished in that the multicopters transmit the positions r_B of the center of gravity B and/or the time derivatives: $\dot{r}_B$ and/or $\ddot{r}_B$ and/or the 3D orientation o_M and/or its time derivative $\dot{o}_M$ of the respective multicopter and/or the force screws τ_e acting externally on the respective multicopter and/or the aerodynamic power $P_{a,n}$ to the respective other multicopters.

One advantageous refinement of the proposed system is distinguished in that one or more multicopters and/or a control center, which is configured for the data exchange with the multicopters in the data network, is/are configured and embodied to solve an optimization problem according to claim 2. This enables in particular the proposed system to be used as a distributed wind estimator, in which a corresponding equation system is prepared, which takes into consideration all or some of the multicopters (agents), and an optimization problem is solved, for example, as in present claim 2. The learning of the regression via the exemplary above-mentioned methods can also be applied to the multicopter scenario.

Further advantages, features, and details result from the following description in which – possibly with reference to the drawings – at least one exemplary embodiment is described in detail. Identical, similar, and/or functionally-identical

parts are provided with identical reference signs.

In the figures:

- 5 Figure 1 shows a diagram to illustrate the variables used to describe the dynamics of the multicopter,
- Figure 2 shows a schematic illustration of the construction of a multicopter according to the invention, and
- Figure 3 shows a schematic illustration of a flow chart of a method according to the invention.

Figure 1 shows a diagram to illustrate the variables and reference systems used to describe the dynamics of the multicopter. The reference system B of the multicopter is located at the position r having an orientation $\bar{R}$ in the inertial system I and is subjected to the wind speed v_w . This wind generates, due to aerodynamic forces in dependence on the relative speed v_r of the multicopter in relation to the air, an external force screw $\tau_e = [f_e^T, \bar{m}_e^T]^T$. The propellers rotate at an angular speed $\varpi = [\varpi_1, \varpi_2, \varpi_3, \varpi_4]^T$ and generate a target force screw $\tau = [f^T, \bar{m}^T]^T$ due to the thrusts T_i and friction torques Q_i . The other cumulative specifications are self-explanatory in conjunction with the above description.

Figure 2 shows a schematic illustration of the construction of a multicopter according to the invention. In the present case, the multicopter comprises a number $N = 4$ electric motors MOT_n for driving $N = 4$ propellers $PROP_n$, a first interface **101** for providing first parameters P1 comprising: a 3D position $r_B = (x_b, y_b, z_b)$ of the center of gravity B of the multicopter, the time derivatives: $\dot{r}_B$ and $\ddot{r}_B$, a 3D orientation $o_M = (\alpha_M, \beta_M, \gamma_M)$ of the multicopter and its time derivative $\dot{o}_M$, a second interface **102** for providing an aerodynamic power $P_{a,n}$ currently generated by the respective propellers $PROP_n$, and a first unit **103**, which, on the basis of the first parameters P1, on the basis of a provided model M1 for describing dynamics of the multicopter, and an estimation determined on the basis of the model M1 of a force screw τ_e acting externally on the multicopter, determines horizontal components $(v_{r,x}, v_{r,y})$ of a relative speed $v_r := (v_{r,x}, v_{r,y}, v_{r,z})^T$ of the multicopter in relation to the air.

The multicopter furthermore comprises a second unit **104**, which, on the basis of the determined horizontal components $(v_{r,x}, v_{r,y})$ and on the basis of the aerodynamic power $P_{a,n}$, determines the vertical component $(v_{r,z})$ of the relative speed v_r , a third unit **105**, which, on the basis of the determined horizontal components $(v_{r,x}, v_{r,y})$, the vertical component $(v_{r,z})$, and on the basis of the parameters P1, determines the wind speed v_w in an inertial system, a storage unit **106** for storing the wind speeds $v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ determined for the locations r_B and a transmission unit **107** for the wireless transmission of the wind speed $v_w(r_B)$ to a receiver (not shown).

Figure 3 shows a schematic illustration of a flow chart of a method according to the invention for measuring a wind speed v_w using a multicopter, wherein the multicopter has a number N of electric motors MOT_n for driving N propellers $PROP_n$, where $n = 1, 2, \dots, N$ and $N \geq 2$. The method comprises the following steps. In a step **201** a provision is performed of first time-dependent parameters P1 comprising a 3D position $r_B = (x_b, y_b, z_b)$ of the center of gravity B of the multicopter, the time derivatives: $\dot{r}_B$ and $\ddot{r}_B$, a 3D orientation $o_M = (\alpha_M, \beta_M, \gamma_M)$ of the multicopter, and the time derivative $\dot{o}_M$. In a further step **202**, a provision is performed of an aerodynamic power $P_{a,n}$ generated by the respective propellers $PROP_n$. In a further step **203**, on the basis of the first parameters P1, a provided model M1 for describing dynamics of the multicopter, and an estimation determined on the basis of the model M1 of a force screw τ_e acting externally on the multicopter, a determination is performed of horizontal components $(v_{r,x}, v_{r,y})$ of a relative speed v_r of the multicopter in relation to the air. In a further step **204**, on the basis of the determined horizontal components $(v_{r,x}, v_{r,y})$ and the aerodynamic power $P_{a,n}$, a determination of the vertical component $(v_{r,z})$ of the relative speed v_r , on the basis of the determined relative speed $v_r = (v_{r,x}, v_{r,y}, v_{r,z})$ and on the basis of the parameters P1, a determination is performed of the wind speed v_w in an inertial system. In a further step **205**, a storage is performed of the wind speed: $v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ determined for r_B . In a further step **206**, a transmission is performed of the wind speed: $v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ to a receiver.

Although the invention was illustrated and explained in greater detail by the preferred exemplary embodiments, the invention is not thus restricted by the disclosed examples and other variations can be derived therefrom by a person skilled in the art without leaving the scope of protection of the invention. it is therefore clear that a variety of possible variations exists. It is also clear that embodiments mentioned by way of example actually only represent examples which are not to be interpreted in any way as a delimitation of, for example, the scope of protection, the possible applications, or the configurations of the invention. Rather, the above description and the description of the figures make a person skilled in the art capable of implementing the exemplary embodiments in concrete form, wherein a person skilled in the art, aware of the disclosed concept of the invention, can perform manifold modifications, for example, with respect to the function or the arrangement of individual elements mentioned in an exemplary embodiment, without leaving the scope of protection which is defined by the claims and the legal equivalents thereof, for example, more extensive explanations in the description.

List of reference numerals

	101	first interface
	102	second interface
5	103	first unit
	104	second unit
	105	third unit
	106	storage unit
	107	transmission unit
10	201-206	method steps

Claims

1. A multicopter having:

- 5 - a number N of electric motors MOT_n for driving N propellers $PROP_n$, where $n = 1, 2, \dots, N$ and $N \geq 2$,
- a first interface (101) for providing first parameters $P1$ comprising: a 3D position $r_B = (x_b, y_b, z_b)$ of the center of gravity B of the multicopter, the time derivatives: $\dot{r}_B$ and $\ddot{r}_B$, a 3D orientation $o_M = (\alpha_M, \beta_M, \gamma_M)$ of the
10 multicopter and its time derivative $\dot{o}_M$,
- a second interface (102) for providing an aerodynamic power $P_{a,n}$ currently generated by the respective propellers $PROP_n$,
- a first unit (103), which, on the basis of the first parameters $P1$ and/or on the basis of a provided model $M1$ for describing dynamics of the
15 multicopter, and/or an estimation determined on the basis of the model $M1$ of a force screw τ_e acting externally on the multicopter, determines horizontal components $(v_{r,x}, v_{r,y})$ of a relative speed $v_r := (v_{r,x}, v_{r,y}, v_{r,z})^T$ of the multicopter in relation to the air,
- a second unit (104) which, on the basis of the determined horizontal components $(v_{r,x}, v_{r,y})$ and on the basis of the aerodynamic power $P_{a,n}$,
20 determines the vertical component $(v_{r,z})$ of the relative speed v_r ,
- a third unit (105), which, on the basis of the determined horizontal components $(v_{r,x}, v_{r,y})$, the vertical component $(v_{r,z})$, and also on the basis of the parameters $P1$ determines the wind speed v_w in an inertial system,
25 system,
- a storage unit (106) for storing the wind speeds $v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ determined for the locations r_B and/or a transmission unit (107) for the wireless transmission of the wind speed $v_w(r_B)$ to a receiver.

30

2. The multicopter as claimed in claim 1,

in which the first unit (103) or the second unit (104) is embodied and configured to solve the following nonlinear quadratic minimization problem for a number of a total of K measurements of the aerodynamic power $P_{a,n}$

for f where $k = 1, \dots, K$ and $k \geq 1$:

$$(1) \quad \bar{f} = \frac{1}{2} F^T F$$

wherein the following applies:

$$(2) \quad F(v_{r,x}, v_{r,y}, v_{r,z}, v_{i,1}, v_{h,1}, P_{a,1}, \dots, v_{i,K}, v_{h,K}, P_{a,K}) = 0,$$

5

$$(3) \quad F = [F_{1,1}, F_{2,1}, F_{3,1}, \dots, F_{1,K}, F_{2,K}, F_{3,K}],$$

$$(4) \quad F_{1,K} = v_{i,k}^4 - 2v_{i,k}^3 v_{r,z} + v_{i,k}^2 (v_{r,x}^2 + v_{r,y}^2 + v_{r,z}^2) - v_{h,k}^4 = 0$$

$$(5) \quad F_{2,k} = v_{i,k} U_k (v_{i,k} - v_{r,z}) - P_{a,k} / (2\rho A_n) = 0$$

$$(6) \quad F_{3,k} = v_{h,k}^2 (v_{i,k} - v_{r,z}) - P_{a,k} / (2\rho A_n) = 0$$

$$(7) \quad U_k = \sqrt{v_{r,x}^2 + v_{r,y}^2 + (v_{i,k} - v_{r,z})^2}$$

10

where

A_n : area swept by the n -th propeller,

ρ : air density,

$v_{h,k}(P_{a,n,k})$: induced speed of the n -th propeller in hovering flight for the k -th measurement,

15

$v_{i,k}(P_{a,n,k})$: speed induced by the n -th propeller for the k -th measurement.

3. The multicopter as claimed in claim 2,

wherein the first unit (103) or the second unit (104) is embodied and configured in such a way that a determined horizontal component ($v_{r,x}, v_{r,y}$) of the relative speed v_r is taken into consideration in the nonlinear quadratic minimization problem by the following relationships:

20

$$(9) \quad F_{4,k} = v_{r,x,k} - v_{r,x} = 0$$

$$(10) \quad F_{5,k} = v_{r,y,k} - v_{r,y} = 0.$$

25

4. The multicopter as claimed in any one of claims 2 to 3,

in which in the first unit (103), the model M1 is based on the following movement equation or the model M1 can be traced back to the following movement equation:

30

$$(11) \quad M\dot{v} + C(v)v + g_M = J^T \tau + \tau_e$$

wherein the following applies: $\tau_e = \tau_d(v_r)$ and $v_r = \dot{r}_B - v_w$

	M :	generalized mass of the multicopter
	v :	generalized speed $[\dot{r}_b^T, \dot{\omega}^T]$
	ω :	angular speed of the multicopter
	$\dot{v}$:	time derivative of v
5	$C(v)$:	$= \begin{bmatrix} 0_{3 \times 3} & 0_{3 \times 3} \\ 0_{3 \times 3} & -(I\omega) \times \end{bmatrix}$
	gM :	weight of the multicopter
	J :	block diagonals of the Jakobi matrix
	τ :	target force screw $[f^T, m^T]$ to be generated by the electric motors MOT_n
10	τ_e :	force screw $[f_e^T, m_e^T]$ acting externally on the multicopter
	$\tau_d(v_r)$:	external force screw generated exclusively by air friction
	v_r :	$= (v_{r,x}, v_{r,y}, v_{r,z})^T$ relative speed of the multicopter in relation to the air
	v_w :	$= (v_{w,x}, v_{w,y}, v_{w,z})^T$ wind speed.

- 15
5. The multicopter as claimed in any one of claims 1 to 4,
in which a control system for controlling and regulating the electric motors MOT_n is provided, wherein the control system is embodied and configured in such a way that the electric motors MOT_n are regulated in such a way
- 20 that the projection of the wind speed v_w on the direction of the axis of rotation of the propellers $PROP_n$ is maximized.
6. The multicopter as claimed in any one of claims 1 to 5,
in which, to determine the aerodynamic power $P_{a,n}$ per electric motor MOT_n ,
- 25 a motor current sensor, a motor rotational speed sensor, or a motor rotational speed estimator are provided, and also a unit which, on the basis of a predetermined model M2 to describe the propeller dynamic range, the detected motor currents and motor rotational speeds, determines the aerodynamic power $P_{a,n}$.
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7. A method for measuring a wind speed v_w using a multicopter, wherein the multicopter has a number N of electric motors MOT_n for driving N propellers

PROP_n, where $n = 1, 2, \dots, N$ and $N \geq 2$, comprising the following steps:

- providing (201) first time-dependent parameters P1 comprising: a 3D position $r_B = (x_b, y_b, z_b)$ of the center of gravity B of the multicopter, the time derivatives: $\dot{r}_B$ and $\ddot{r}_B$, a 3D orientation $o_M = (\alpha_M, \beta_M, \gamma_M)$ of the multicopter and its time derivative $\dot{o}_M$,
- providing (202) an aerodynamic power $P_{a,n}$ generated by the respective propellers PROP_n,
- on the basis of the first parameters P1 and/or a provided model M1 for describing dynamics of the multicopter and/or an estimation determined on the basis of the model M1 of a force screw τ_e acting externally on the multicopter, determining (203) horizontal components $(v_{r,x}, v_{r,y})$ of a relative speed v_r of the multicopter in relation to the air,
- on the basis of the determined horizontal components $(v_{r,x}, v_{r,y})$ and the aerodynamic power $P_{a,n}$, determining (204) the vertical component $(v_{r,z})$ of the relative speed v_r , on the basis of the determined relative speed $v_r = (v_{r,x}, v_{r,y}, v_{r,z})$ and on the basis of the parameters P1, determining the wind speed v_w in an inertial system, and
- storing (205) the wind speed $v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ determined for r_B and/or transmitting (206) the wind speed: $v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ to a receiver.

8. The method as claimed in claim 7,
in which a control system for controlling and regulating the electric motors MOT_n is provided, wherein the electric motors MOT_n is regulated in such a way that the projection of the wind speed v_w on the direction of the axis of rotation of the propellers is maximized.

9. The method as claimed in any one of claims 7 to 8,
in which to determine the aerodynamic power $P_{a,n}$ per electric motor MOT_n, a motor current and a motor rotational speed are determined, and, on the basis of a predetermined model M2 for describing the propeller dynamic range, the detected motor currents and motor rotational speeds, the aerodynamic power $P_{a,n}$ is determined.

10. A computer system having a data processing device, wherein the data processing device is designed in such a way that a method as claimed in any one of claims 7 to 9 is executed on the data processing device.

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11. A system comprising two or more multicopters as claimed in any one of claims 1 to 6,

wherein the multicopters are each embodied and configured for data exchange with one another in a data network and the multicopters transmit the respective determined wind speed: $v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ to the respective other multicopters.

12. The system as claimed in claim 11,
wherein the multicopters are embodied as agents or softbots for wireless communication in the data network.

13. The system as claimed in any one of claims 11 to 12, comprising two or more of the multicopter as claimed in claim 5,
in which the control system for controlling and regulating the electric motors MOT_n of the respective multicopter is embodied and configured in such a way that determined wind speeds transmitted from the other multicopters: $v_w(r_B) = (v_{w,x}(r_B), v_{w,y}(r_B), v_{w,z}(r_B))$ are taken into consideration in the regulation.

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14. The system for as claimed in any one of claims 11 to 13,
wherein the multicopters transmit the positions r_B of the center of gravity B and/or the time derivatives: $\dot{r}_B$ and/or $\ddot{r}_B$ and/or the 3D orientation o_M and/or its time derivative $\dot{o}_M$ of the respective multicopter and/or the force screws τ_e acting externally on the respective multicopter and/or the aerodynamic power $P_{a,n}$ to the respective other multicopters.

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