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- (54) **DRONE DETECTION AND INTERCEPTION**
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See application file for complete search history.

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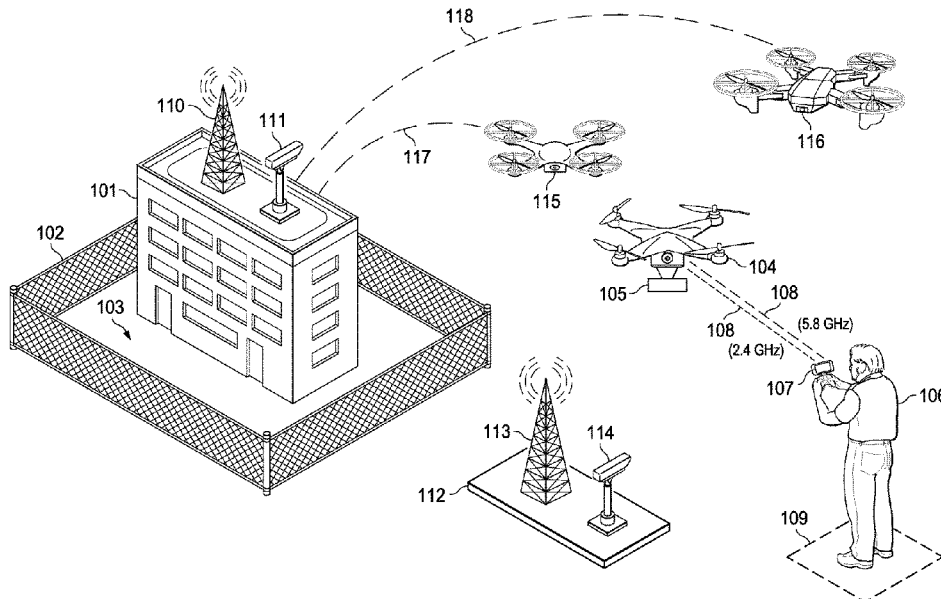
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(57) **ABSTRACT**

Embodiments disclosed herein provide for systems and methods for detecting and intercepting drones and drone operators. An example system for disrupting drone attacks comprises a drone detection system configured to detect a hostile drone, a defensive drone control system coupled to the drone detection system and configured to communicate with a first defensive drone, and a first defensive drone configured to receive first data from the defensive drone control system and to use the data to intercept the hostile drone. The system for disrupting drone attacks may further comprise a system configured to identify a control source of the hostile drone, and a second defensive drone configured to receive second data from the defensive drone control system and to use the second data to fly to a location associated with the control source of the hostile drone.

20 Claims, 3 Drawing Sheets



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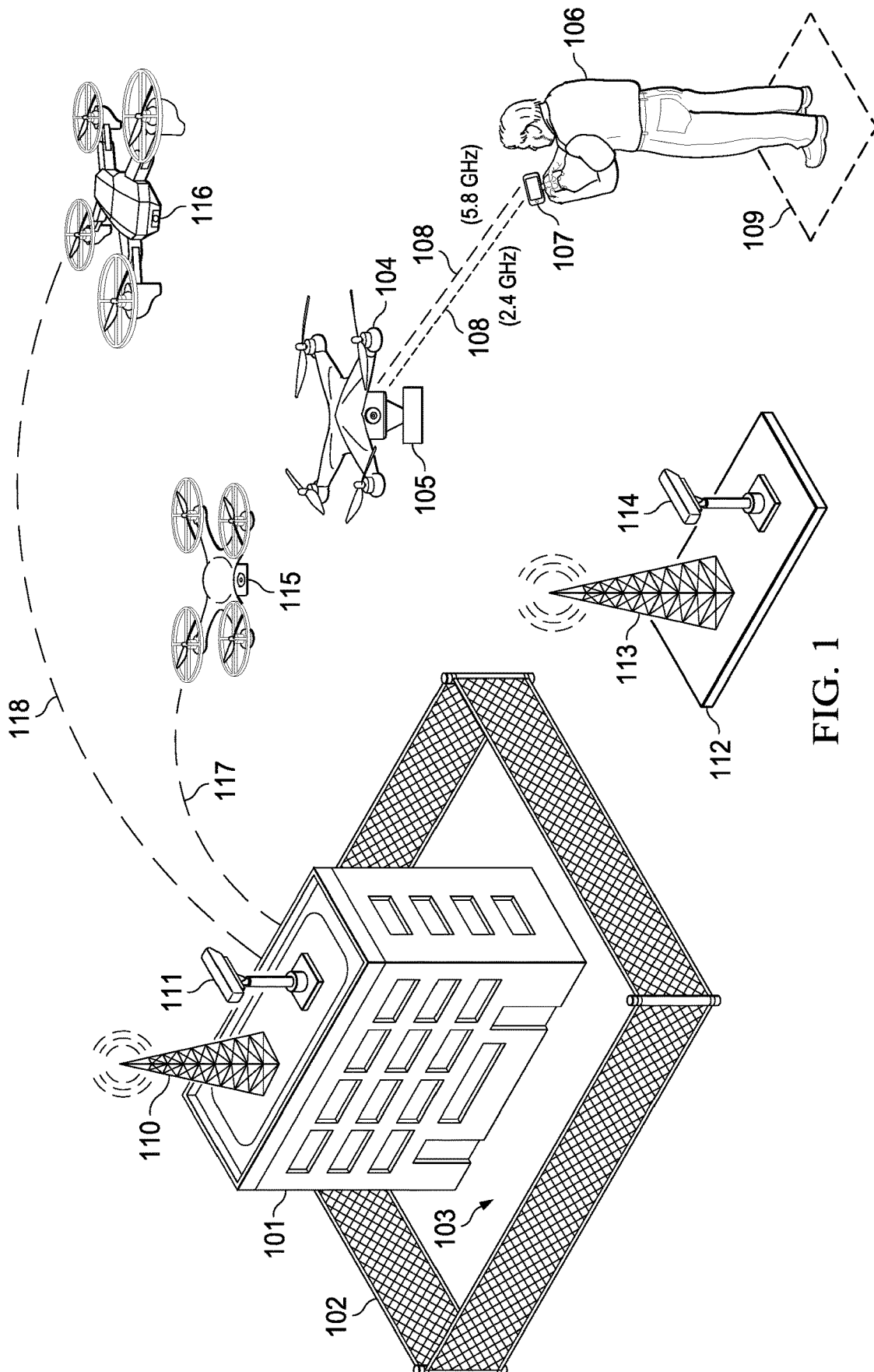


FIG. 1

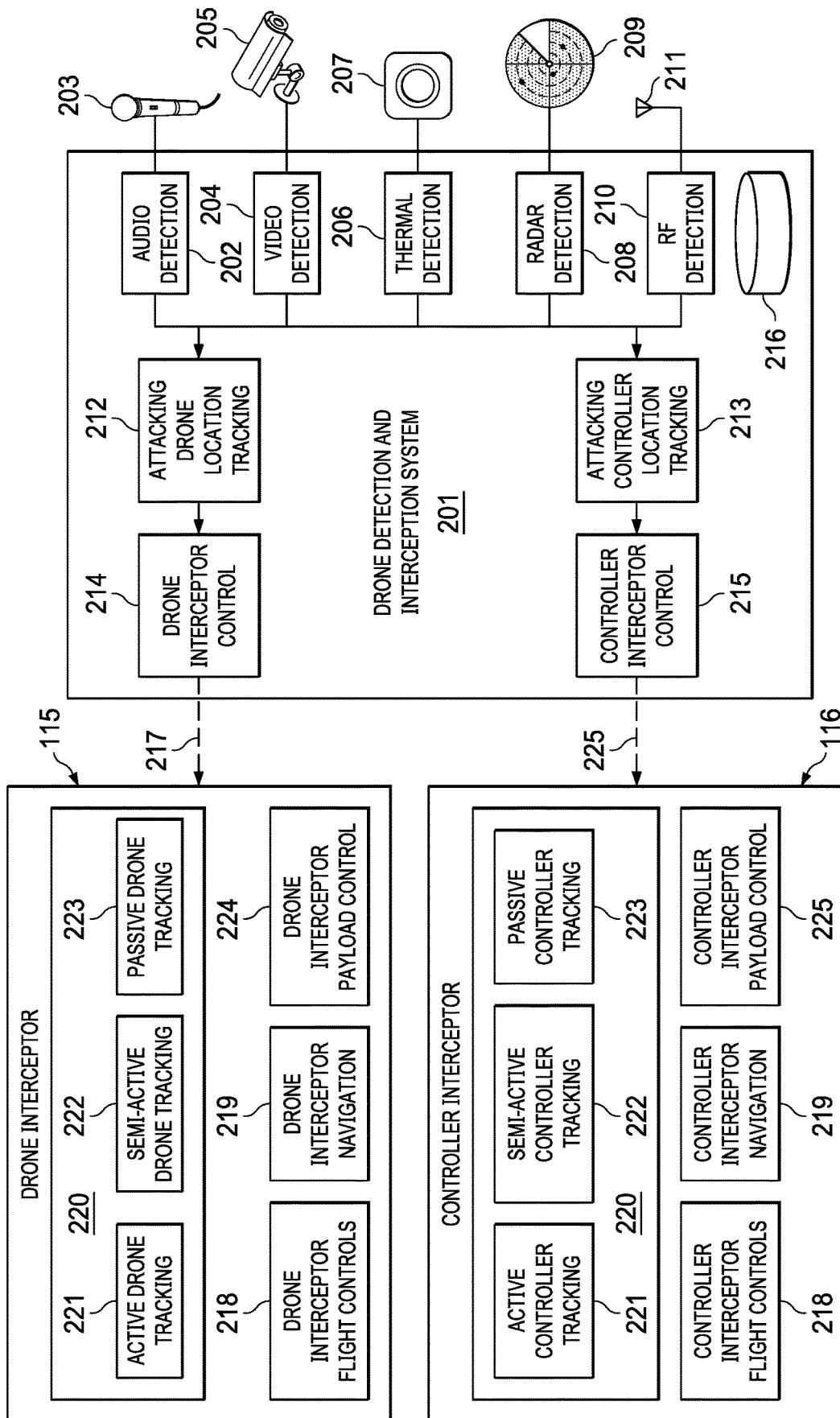


FIG. 2

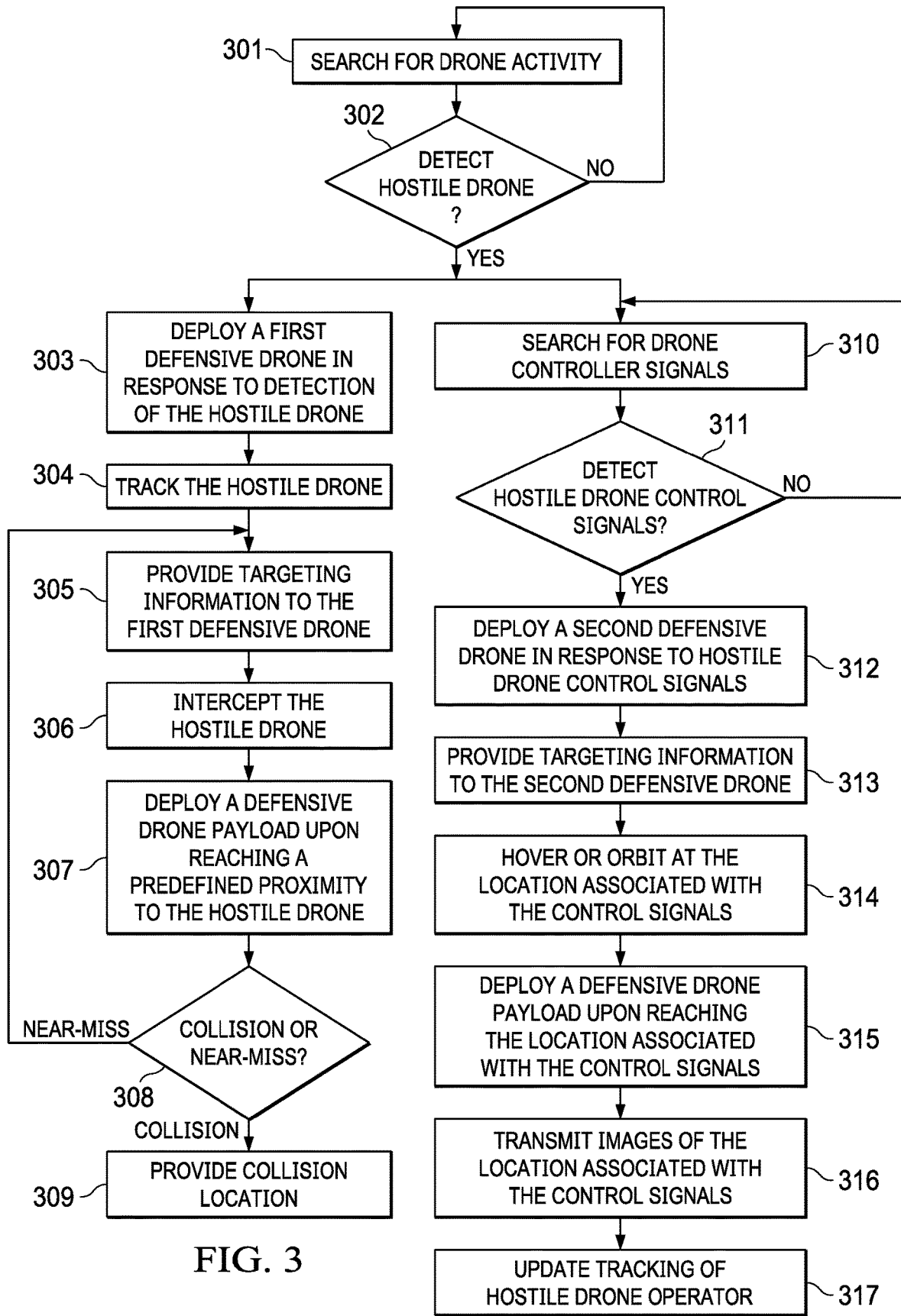


FIG. 3

DRONE DETECTION AND INTERCEPTION

TECHNICAL FIELD

The present disclosure relates to detection and interception of drone or remotely controlled aircraft within the vicinity of controlled-environment facilities.

BACKGROUND

Remote-controlled aircraft have become popular in recent years due to the availability of relatively cheap recreational models with improved flight characteristics that can be controlled by almost anyone. Small scale, private unmanned aircraft, including Unmanned Aerial Vehicles (UAVs), are commonly referred to as “drones” and are typically controlled using radio frequency devices. The controller may be a dedicated control device, but can also be a smartphone, tablet computing device, or the like. For example, tablet computing devices or smartphones may employ an application program to provide such control, employing the radio and/or Global Positioning System (GPS) functionality of the cell phone or tablet computing device to transmit signals to the drone and using the screen of the device to provide feedback to the user. The ubiquity of the mass consumer and inexpensive drone aircraft is a potential risk to controlled-environment facilities that have a need to limit access for security, safety, and/or privacy concerns. Media reports of negligent, criminal, and/or malicious drone use around airports, military bases, and prisons have become a common occurrence.

Drones are remotely controlled using radio frequency transmissions. Technology exists that could be used to jam cellular, radio, and WiFi signals around a controlled-environment facility thereby preventing drones from being controlled by their operator. However, the Federal Communications Commission (FCC) explicitly forbids the use of such technology to prevent interference with valid uses of other cellular, radio, and WiFi signals. Drone countermeasures, such as net guns, require a defender to be in position to manually identify and target the drone. This typically means that the defender is located at the target site and that the drone is not stopped before reaching the target. Accordingly, other methods of dealing with unwanted and/or malicious drone activity must be employed.

SUMMARY

Embodiments disclosed herein provide for systems and methods for detecting and intercepting drones and drone operators. An example system for disrupting drone attacks comprises a drone detection system configured to detect a hostile drone, a defensive drone control system coupled to the drone detection system and configured to communicate with a first defensive drone, and a first defensive drone configured to receive first data from the defensive drone control system and to use the data to both track and intercept the hostile drone. The system for disrupting drone attacks may further comprise a system configured to identify a control source of the hostile drone, and a second defensive drone configured to receive second data from the defensive drone control system and to use the second data to fly to a location associated with the control source of the hostile drone. The drone detection system may detect the hostile drone using one or more of audio detection, visual detection, thermal detection, radar detection, or radio frequency detection.

The first defensive drone concludes an interception by a collision with the hostile drone or by a near-miss with the hostile drone. The first defensive drone may carry a payload, and may deploy the payload upon reaching a predefined proximity to the hostile drone. The first defensive drone comprises a tracking system configured to allow the first defensive drone to self-track the hostile drone.

The second defensive drone is configured to hover or orbit at the location associated with the control source of the hostile drone. The second defensive drone carries a payload and deploys the payload upon reaching the location associated with the control source of the hostile drone. The second defensive drone comprises a navigation system configured to allow the second defensive drone to self-navigate to the location associated with the control source of the hostile drone. The second defensive drone comprises a camera configured to transmit images and a geo-tracking or navigation system to transmit the coordinates of the location associated with the control source of the hostile drone to the defensive drone control system.

BRIEF DESCRIPTION OF THE DRAWINGS

Having thus described the invention in general terms, reference will now be made to the accompanying drawings, which are not necessarily drawn to scale, and wherein:

FIG. 1 is a block diagram illustrating a drone detection and interception system according to an example embodiment.

FIG. 2 is block diagram illustrating a system for drone detection and interception according to one embodiment.

FIG. 3 is a flowchart illustrating a process for disrupting drone attacks according to one embodiment.

DETAILED DESCRIPTION

The invention now will be described more fully hereinafter with reference to the accompanying drawings. This invention may, however, be embodied in many different forms and should not be construed as limited to the embodiments set forth herein. Rather, these embodiments are provided so that this disclosure will be thorough and complete, and will fully convey the scope of the invention to those skilled in the art. One skilled in the art may be able to use the various embodiments of the invention.

FIG. 1 is a block diagram illustrating a drone detection and interception system according to an example embodiment. Controlled-environment facility **101** may be any building, group of buildings, compound, acreage, campus, base, or station that provides limited and controlled access for security, safety, and/or privacy reasons. For example, controlled-environment facility **101** may be a government building, military base, prison, jail, school, airport, train station, or corporate, educational, or medical campus. Controlled-environment facility **101** may be protected by a fence **102** or other man-made or natural barricade that restricts access to facility **101** and surrounding grounds **103**. However, fence **102** has limited effectiveness and cannot keep out objects that go over fence **102**, such as items thrown or flown over fence **102**. Accordingly, such facilities **101** may be subject to drone attacks as part of terroristic, malicious, and/or criminal activity. Reports of drones interfering with aircraft and airport flight operations are common. Terrorist groups have used drones to drop grenades on military facilities. Drones have also been used to deliver contraband, such as drugs, cell phones, and weapons, to prisoners in correctional institutions.

As shown in FIG. 1, an attacking drone **104**, which may have a malicious or contraband payload **105**, can be flown over fence **102**. Once attacking drone **104** is past fence **102**, it can then be flown into a structure at controlled-environment facility **101** and/or drop payload **105** in surrounding area **103**. Attacking drone **104** is controlled by an operator **106**, who uses a radio controller **107** to control the flight path and activities of drone **104**. Attacking drone **104** may be a fixed wing or multi-rotor aircraft type, such as commercially available quadcopter drones.

Controller **107** communicates with attacking drone **104** on one or more frequencies **108**. Common frequency bands for controlling commercial drones are 2.4 GHz and 5.8 GHz. Commercial drones often have camera that allows operator **106** to capture aerial video and/or to get a drone's eye-view, which allows operator **106** to fly drone **104** using a first-person view (FPV). To avoid interference, drones use multiple frequencies **108** wherein one frequency is used to control the drone and the other frequency is used for video transmission. Other frequencies, such as 433 MHz, 900 MHz, or 1.2 GHz, may be also be used for drone control and video transmission. Commercial drones typically use spread spectrum transmission techniques on the 2.4 GHz and 5.8 GHz frequencies to minimize interference with nearby drones using the same frequency.

The frequencies **108** used in most commercial drones are considered to be line-of-sight meaning that connection between controller **107** and drone **104** is disrupted when an object (e.g., a building, barrier, or natural feature) comes between the controller **107** and drone **104**. The line-of-sight requirement and the signal strength of controller **107** limits the effective range of drone **104**. Typical hobby drones have a maximum realistic range of 3 to 5 miles; however, specialized controllers are commercially available that support ranges from 20 to 40 miles. Moreover, it will be understood that military, law enforcement, and proprietary drones may be capable of farther ranges and may use other frequencies and/or communication protocols between controller **107** and drone **104** that are less dependent on line-of-sight communications.

Operator **106** launches attacking drone **104** from a location **109** that allows the controller **107** to maintain a radio frequency (RF) connection with drone **104** during the flight from location **109** to target facility **101**. Operator **106** needs minimal space to launch drone **104** and the launch location **109** does not have to be in view of the target facility **101**. This makes it difficult to detect and stop the launch of an attacking drone **104**, which means the drone **104** must be detected and stopped in-flight to prevent it from reaching facility **101**.

In one embodiment, drone-detection systems are installed at controlled-environment facility **101**. These systems may comprise, for example, an antenna **110** that uses active or passive methods to detect attacking drone **104**. Antenna **110** may be part of a radar system that actively scans for drones near controlled-environment facility **101**. Alternatively, antenna **110** may be used to monitor common drone control frequencies to detect when a drone is being operated within RF range of controlled-environment facility **101**. Other detection sensors **111** may also be used, such as microphones, cameras, and thermal sensors, that passively search for sounds, video, and/or heat signatures of a drone **104**. Any one or combination of these search and detection methods may be used along with any other technologies for detecting and monitoring drones.

In addition to the drone-detection systems **110** and **111** installed at controlled-environment facility **101**, other detec-

tion systems may be located at an off-site location **112**. For example, active or passive antenna **113** and/or microphones, cameras, and/or thermal sensors **114** may search for attacking drones **104**. The off-site location **112** may increase the possibility of early detection of drone **104** before it reaches facility **101** and thereby prevent delivery of payload **105**. Off-site location **112** may be selected based on geography, such as to place sensors at a higher elevation, or other factors, such as to place sensors near probable drone-launching areas (e.g., parking lots, open fields). In other embodiments, only the sensors **113** and **114** at remote or off-site location **112** are used instead of using sensors at facility **101**. Alternatively, multiple remote or off-site locations **112** may be used to ensure broad coverage around facility **101**.

Once a drone **104** is detected, a drone detection and interception system may evaluate a threat level for drone **104**. Some controlled-environment facilities **101** may be entirely or partially surrounded by a no-fly zone or a no-drone zone. In this scenario, if drone **104** is in the designated no-fly zone, then it is designated as hostile. In other situations, the drone detection and interception system may evaluate the flight path of drone **104**. If drone **104** is on a flight path directed away from facility **101** or otherwise unlikely to come within a predetermined range of the facility **101**, then the drone **104** may be designated as non-threatening. However, drones on a flight path toward or near facility **101** may be designated as threatening. Once the drone **104** has been detected and evaluated, the drone detection and interception system may then act based on the threat level. For low-level or non-threatening drones **104**, the drone detection and interception system may continue monitoring and reevaluating drone **104**. Once the drone **104** is designated as attacking or otherwise threatening, the drone detection and interception system may act to oppose attacking drone **104**.

The drone detection and interception system may launch one or more defensive drones **115** and **116** in response to an attacking drone **104**. Drones **115** and **116** may be launched from controlled-environment facility **101**, remote location **112**, and/or any other appropriate staging location. Drones **115** and **116** may both be launched from the same location or may be launched from different locations. There may be multiple defensive drone launch locations at or near facility **101**. At each defensive drone launch location, there may be multiple defensive drones on standby for launch to oppose an attacking drone **104**. In another embodiment, standby defensive drones **115** and/or **116** may be launched before a threat is detected and may be maintained in an airborne holding pattern to minimize response time. The drone detection and interception system can counterattack an attacking drone **104** that is approaching from any direction and/or counterattack multiple attacking drones **104**.

Drone **115** is a drone interceptor that is directed by the drone detection and interception system to intercept and collide with attacking drone **104**. Drone **115** may be remotely controlled all the way to impact by control signals **117**. Alternatively, the drone detection and interception system may guide drone **115** until it acquires attacking drone **104**, and then drone **115** is self-guided to intercept and hit drone **104**. The mass and/or speed of drone **115** may be selected to increase the likelihood that attacking drone **104** is damaged and knocked out of the air following impact. Additionally, drone **115** may be hardened or otherwise designed to withstand an impact so that it can continue to pursue attacking drone **104** and inflict additional impacts on drone **104**, if needed. Drone **115** may also carry a payload

that can be used against attacking drone **115**, such as an explosive warhead or objects/liquid that can be dropped on attacking drone **115** to cause it to crash.

Drone **116** is a controller/operator interceptor that is directed by the drone detection and interception system to detect, identify, and highlight operator **106** and/or controller **107**. Drone **116** may be remotely controlled all the way to location **109** using control signals **118** and/or may be self-guided to location **109**. The operator **106** and/or controller **107** may be detected and tracked using, for example, the remote-control signals **108** between drone **104** and controller **107**. Drone **116** may track or home in on signals **108** back to their source. Once drone **116** is above location **109**, it may covertly or overtly hover in that location to highlight operator **106**. Additionally, drone **116** may carry a camera and/or a geo-tracking system that would allow a remote operator at facility **101** or at location **112** to observe and receive location coordinates to search the general area around location **109** to identify operator **106**. Once operator **106** has been identified, law enforcement or other personnel can go to location **109** to interview, arrest, or otherwise interact with operator **106**. Drone **116** may also carry a payload that can be used to highlight location **109**, such as lights, flares, or smoke. If operator **106** attempts to flee location **109** on foot or in a vehicle, drone **116** can follow operator **106** to assist investigating personnel in tracking and catching operator **106**. Drone **116** may also provide geolocation coordinates for operator **106** to the investigating personnel.

FIG. 2 is block diagram illustrating a system for drone detection and interception according to one embodiment. Drone detection and interception system **201** may be configured to protect a controlled-environment facility or any other location from drone attacks. Drone detection and interception system **201** may use a plurality of different drone detection and tracking technologies.

Audio detection subsystem **202** may use one or more microphones **203** that capture sound near the controlled-environment facility. The sound may be processed in real-time to search for audible and inaudible sounds at frequencies associated with drone aircraft, such as engine or propeller noises. An array of directional microphones **203** may be used to determine a general direction from which such sounds are detected and thereby identify a probable direction of a drone attack. The sensitivity of the microphones **203** and the volume of the noise source will determine the distance at which a drone can be detected using audio detection **202**.

Video detection subsystem **204** may comprise one or more cameras **205** that capture images near the controlled-environment facility. The video frames may be processed in real-time to search for images that are associated with drone aircraft, such as shapes that match drone silhouettes from different perspectives. Alternatively, an object's motion across several frames may be analyzed to detect and identify drone flight patterns, which may be useful to screen out birds, balloons, airplanes, or other nonthreatening objects. An array of cameras **205** may be used to cover all directions around the controlled-environment facility simultaneously.

Thermal detection subsystem **206** may comprise one or more heat sensitive detectors **207** that capture, for example, infrared images near the controlled-environment facility. The infrared images may be processed in real-time to search for objects that are hotter than the surrounding area or background. Certain infrared frequencies may be associated with drone aircraft to help distinguish drones from other objects. This method of detecting drones may be more successful to detect gas-engine powered drones, which are

likely to operate at hotter temperatures than drones with electric motors. An array of heat sensors **207** may be used to cover all directions around the controlled-environment facility simultaneously.

Radar detection subsystem **208** may comprise an antenna **209** that uses radio signals to search near the controlled-environment facility. The contacts detected may be processed in real-time to search for objects that may be drone aircraft. Radar signals that are sensitive enough to detect drone aircraft may also detect birds, so an object's motion over time may need to be analyzed to distinguish drone flight patterns from birds. The small radar cross-section of most drone aircraft may limit the effective range and usefulness of radar detection.

Radio Frequency (RF) detection subsystem **210** may comprise one or more antennas **211** that capture RF signals near the controlled-environment facility. The RF signals may be processed in real-time to search for signals that are associated with drone aircraft. The signals used to remotely control commercial drones operate on known frequencies. These signals originate from a drone controller, which is associated with the location of the drone operator. Also, the frequencies used to transmit video from the drone to the controller are often known and originate from the location of the drone itself. For example, a drone controller may broadcast control signals on 5.8 GHz, while the drone transmits video signals on 2.4 GHz, or vice versa. An array of antennas **211** may be used to determine a direction from which the drone-related RF signals originate to provide at least a relative bearing to the attacking drone or controller.

Detection subsystems **202**, **204**, **206**, **208**, and **210** and sensors **203**, **205**, **207**, **209**, and **211** may be located at the controlled-environment facility and/or at other locations (such as facility **101** and/or location **112**, FIG. 1). Detection subsystems **202**, **204**, **206**, **208**, and **210** provide inputs to location tracking subsystems **212** and **213**. The attacking drone location tracking subsystem **212** uses these inputs to identify and track an attacking drone. Tracking subsystem **212** may receive one or more inputs and correlate those inputs to identify an airborne object approaching the controlled-environment facility. For example, captured sounds, thermal signatures, or RF signals along with visual silhouettes or radar cross-sections may be correlated to identify an attacking drone. Similarly, tracking subsystem **213** may receive one or more inputs and correlate those inputs to identify a drone controller near the controlled-environment facility. For example, received RF signals may be correlated to drone control signals. Sensors **203**, **205**, **207**, **209**, and **211** may provide at least a direction or bearing to the attacking drone. Radar detection subsystem **208** may also provide a range or distance to determine a precise position for the attacking drone. In other embodiments, bearings from two or more detection subsystems **202**, **204**, **206**, **208**, and **210** may be used by location tracking subsystems **212** and **213** to triangulate the attacking drone's position. Detection subsystems **202**, **204**, **206**, **208**, and **210** may provide both an azimuth and elevation for the bearing to the attacking drone.

Drone detection and interception system **201** uses the drone and controller location information from tracking subsystems **212** and **213** to control defensive drones that are used to intercept the attacking drone and to locate the attacking drone's operator. Attacking drone location tracking **212** provides inputs to drone interceptor control **214**, which generates control signals for a defensive drone (e.g., drone **115**, FIG. 1) that is sent after the attacking drone. Attacking controller location tracking **213** provides inputs to controller interceptor control **215**, which generates control

signals for a defensive drone (e.g., drone **116**, FIG. 1) that is sent after the operator who is using the attacking drone controller.

Drone detection and interception system **201** may have a library of known drone and/or controller profiles **216**, such as sounds, thermal signatures, visual silhouettes, radar cross-sections, and/or RF signals associated with known drones. If detected drone or controller information is correlated to a known drone profile, then the function of location tracking subsystems **212** and **213** and interceptor control subsystems **214** and **215** may be enhanced. For example, if the attacking drone's capabilities (e.g., speed, range, maneuverability) are known from a profile, the operation of the attacking drone can be more accurately predicted and anticipated during an intercept.

Drone intercept control **214** sends control signals **217** to direct drone interceptor **115** to intercept and impact the attacking drone (e.g., drone **104**). Drone interceptor **115** includes flight control system **218** for controlling drone maneuvering, navigation system **219** for managing current and destination locations, and tracking system **220** for targeting an attacking drone. Drone intercept control **214** may provide real-time control inputs (e.g., pitch, roll, throttle, etc.) to flight control system **218**. Alternatively, drone intercept control **214** may provide a current location of the attacking drone, and drone interceptor **115** may use geo-tracking or navigation system **219**, such as a GPS system, to fly to that location.

Tracking system **220** may also be used to direct drone interceptor **115** to the attacking drone using one or more of active tracking **221**, semi-active tracking **222**, or passive tracking **223**. Active tracking **221** is any self-contained tracking device on drone **115**, such as an onboard radar system that transmits and receives radar signals. Semi-active tracking **222** uses signals reflected from the target as guidance. For example, the drone detection and interception system **201** may target an attacking drone using a radar or laser signal, and the reflected radar or laser energy is used to guide drone **115**. Passive tracking **223** uses information, such as noise or heat radiated by the attacking drone itself, to track the attacking drone. Passive tracking **223** may also use a camera to track a visual image of the attacking drone. Drone interceptor **115** may use any appropriate technique, such as pure, lead, or lag pursuit, to intercept the attacking drone. The intended conclusion of the intercept by drone **115** is to create an actual, physical collision with the attacking drone. The location of the collision and/or the location of the crashed attacking drone is reported back to the drone detection and interception system **201** so that personnel can be dispatched to recover the attacking drone and its payload for analysis and investigation.

In addition to an actual collision or impact between the drone interceptor **115** and the attacking drone, other means may be used to increase the chances of downing the attacking drone. These may be used in the event of a near miss or in addition to a collision intercept. A payload control **224** manages deployment of a payload carried by drone interceptor **115**. The payload may be, for example, an explosive warhead, objects (e.g., nets, sticks, wire, ropes, etc.), or liquid (e.g., water, paint, etc.) that can be dropped or sprayed on attacking drone **115** to cause it to crash. The explosive warhead may be nonlethal to humans, but lethal to flying objects, such as by ejecting or dropping low-speed shrapnel that would not harm a person but would damage a drone operating at flying speed. If drone interceptor **115** deploys its payload at or near the expected point of collision, the payload may still cause the attacking drone to crash even if

there was a near-miss. For example, if nets or other objects get entangled with a propeller, if paint blinds a drone FPV camera, or if water shorts out or stalls an engine, then the attacking drone would likely crash or be uncontrollable.

Controller intercept control system **215** sends signals **225** to cause controller interceptor **116** to locate and identify the operator **106** and/or controller **107**. Control interceptor **116** includes flight controls system **218**, navigation system **219**, and tracking system **220**, which are similar to the components of drone interceptor **115**. Controller intercept control **215** may provide real-time control inputs (e.g., pitch, roll, throttle, etc.) to fly controller interceptor **116** to the operator's location **109**. Alternatively, controller intercept control **215** may provide a current location of the operator **106** or controller **107**, and controller interceptor **116** may use its navigation system **219** to fly itself to that location (e.g., location **109**, FIG. 1). In another embodiment, controller intercept control **215** may provide other identifying information, such a frequency **108** broadcast by the controller **107**, that the controller interceptor **116** can use to home in on the operator **106**.

Rather than collide or impact the operator **106** or controller **107**, the intent of controller interceptor **116** is to locate and identify operator **106**. Controller interceptor **116** may have an onboard camera, for example, for sending images of the location **109** back to the drone detection and interception system **201**. Those images may be analyzed by a user to identify and further track operator **106**. Controller interceptor **116** may also send geolocation coordinates to assist in tracking operator **106**. If operator **106** attempts to flee, controller interceptor **116** can follow and update the operator's position. When the operator **106** is in a relatively stationary position, controller interceptor **116** may hover or orbit near that position. The operator's position can be highlighted using a payload **225** on the controller interceptor to guide security or law enforcement personnel to the operator. For example, controller interceptor **116** may drop flares, smoke, or other markers near location **109**.

FIG. 3 is a flowchart illustrating a process for disrupting drone attacks according to one embodiment. In step **301**, a drone detection and interception system searches for drone activity. Drone activity can be detected using, for example, one or more of audio detection, visual detection, thermal detection, radar detection, or radio frequency detection. In step **302**, the system evaluates if a hostile drone has been detected. If no drones have been detected, or if a drone is determined to be non-hostile, then the process returns to step **301** to continue searching.

In step **303**, a first defensive drone is deployed in response to detection of the hostile drone. In step **304**, the hostile drone is tracked by the drone detection and interception system. The tracking may be achieved by one or more methods, such as using audio, visual, thermal, radar, and/or RF signal tracking. The initial detection and the tracking may be performed at a controlled-environment facility or other potential target of hostile drones. Alternatively, or in addition, the detection and tracking may be performed at a location remote from the controlled-environment facility or other potential target. Tracking from multiple locations may be used to triangulate the hostile drone's location and flight path.

In step **305**, targeting information is provided to the first defensive drone. The targeting information may be configured to control a flight path of first defensive drone in a manner to intercept the hostile drone, such as by remotely controlling the first defensive drone. Alternatively, the targeting information may be configured to allow the first

defensive drone itself to target and track the hostile drone. For example, the first defensive drone may have a tracking and guidance capability to use active, semi-active, or passive tracking of a hostile drone.

In step 306, the first defensive drone intercepts the hostile drone. The first defensive drone may pursue the hostile drone using any appropriate intercept techniques or geometry based upon initial locations, environmental conditions, atmospheric conditions, drone speeds, or other factors. In step 307, a payload is deployed by the first defensive drone upon reaching a predefined proximity to the hostile drone. Preferably, the intercept ends in a collision, but the deployment of a payload, such as an explosive, object, or liquid, will improve the chances that the hostile drone is forced to crash.

In step 308, the drone detection and interception system determines if the intercept ended in a collision or near-miss between first defensive drone and the hostile drone. If the intercept ended in a near-miss or if the hostile drone is not downed, then the process returns to step 305 and the drone detection and interception system provides updated targeting information to the first defensive drone so that it can reacquire the hostile drone and attempt another interception and collision.

In step 309, if the interception ended in a successful collision that downed the hostile drone, a collision location is provided to the drone detection and interception system so that the hostile drone and any payload can be recovered.

When the hostile drone is detected in step 302, in addition to deploying the first defensive drone in step 303, the drone detection and interception system begins searching for hostile drone controller signals in step 310. In step 311, the drone detection and interception system evaluates if hostile drone controller signals have been detected. If no drone controller signals have been detected, then the process returns to step 310 and the searching continues.

In step 312, if hostile drone controller signals have been detected, then a second defensive drone is deployed. In step 313, targeting information is provided to the second defensive drone. The targeting information may be configured to control a flight path of second defensive drone in a manner to fly the second defensive drone to a location associated with the control signals, such as by remotely controlling the second defensive drone. Alternatively, the targeting information may be configured to allow the second defensive drone itself to target and track the location associated with the control signals.

In step 314, the second defensive drone hovers or orbits at the location associated with the control signals. In step 315, a defensive drone payload is deployed by the second drone upon reaching the location associated with the control signals. This payload may be, for example, flares, smoke, or other markers that highlight the location associated with the control signals to aid in directing security or law enforcement personnel to the location. In step 316, images are transmitted from the second defensive drone to the drone detection and interception system of the location associated with the control signals. In step 317, the tracking of the hostile drone operator is updated, such as further location tracking if the operator attempts to flee the original location.

The foregoing has outlined rather broadly the features and technical advantages of the present invention in order that the detailed description of the invention that follows may be better understood. It should be appreciated that the conception and specific embodiment disclosed may be readily utilized as a basis for modifying or designing other structures for carrying out the same purposes of the present

invention. It should also be realized that such equivalent constructions do not depart from the invention as set forth in the appended claims. The novel features which are believed to be characteristic of the invention, both as to its organization and method of operation, together with further objects and advantages will be better understood from the following description when considered in connection with the accompanying figures. It is to be expressly understood, however, that each of the figures is provided for the purpose of illustration and description only and is not intended as a definition of the limits of the present invention.

What is claimed is:

1. A system for disrupting drone attacks, comprising:
 - a drone detection system configured to detect a hostile drone and identify a control source of the hostile drone;
 - a defensive drone control system coupled to the drone detection system and configured to communicate with at least a first and a second defensive drone;
 - the first defensive drone configured to receive first data from the defensive drone control system and to use the first data to intercept the hostile drone; and
 - the second defensive drone configured to receive second data from the defensive drone control system and to use the second data to fly to a location associated with the control source of the hostile drone.
2. The system of claim 1, wherein the drone detection system detects the hostile drone using one or more of audio detection, visual detection, thermal detection, radar detection, or radio frequency detection.
3. The system of claim 1, wherein the first defensive drone concludes an interception by a collision with the hostile drone or by a near-miss with the hostile drone.
4. The system of claim 1, wherein the first defensive drone comprises a payload, and wherein the first defensive drone deploys the payload upon reaching a predefined proximity to the hostile drone.
5. The system of claim 4, wherein the defensive drone control system controls deployment of the payload.
6. The system of claim 1, wherein the first defensive drone comprises a tracking system configured to allow the first defensive drone to self-track the hostile drone.
7. The system of claim 1, wherein the second defensive drone is configured to hover or orbit at the location associated with the control source of the hostile drone.
8. The system of claim 1, wherein the second defensive drone comprises a payload, and wherein the second defensive drone deploys the payload upon reaching the location associated with the control source of the hostile drone.
9. The system of claim 8, wherein the defensive drone control system controls deployment of the payload.
10. The system of claim 1, wherein the second defensive drone comprises a navigation system configured to allow the second defensive drone to self-navigate to the location associated with the control source of the hostile drone.
11. The system of claim 1, wherein the second defensive drone comprises a camera configured to transmit images of the location associated with the control source of the hostile drone to the defensive drone control system.
12. A method for disrupting drone attacks, comprising:
 - detecting a hostile drone;
 - deploying a first defensive drone in response to detection of the hostile drone;
 - tracking the hostile drone;
 - providing first targeting information to the first defensive drone, the first targeting information configured to control a flight path of the first defensive drone in a

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manner to intercept the hostile drone or to allow the first defensive drone to target and track the hostile drone;

intercepting the hostile drone by the first defensive drone;

detecting control signals associated with the hostile drone;

5 deploying a second defensive drone in response to detection of the control signals; and

providing second targeting information to the second defensive drone, the second targeting information configured to control a flight path of the second defensive drone in a manner to fly the second defensive drone to a location associated with the control signals or to allow the second defensive drone to target and track the location associated with the control signals.

13. The method of claim 12, wherein the hostile drone is detected using one or more of audio detection, visual detection, thermal detection, radar detection, or radio frequency detection.

14. The method of claim 12, wherein the first defensive drone concludes an interception by a collision with the hostile drone or by a near-miss with the hostile drone.

15. The method of claim 12, further comprising: deploying a first defensive drone payload upon reaching a predefined proximity to the hostile drone.

16. The method of claim 12, further comprising: hovering or orbiting by the second defensive drone at the location associated with the control signals.

17. The method of claim 12, further comprising: deploying a second defensive drone payload upon reaching the location associated with the control signals.

18. The method of claim 12, further comprising: transmitting from the second defensive drone images of the location associated with the control signals.

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19. A method for disrupting drone attacks, comprising:

detecting a hostile drone and control signals associated with the hostile drone;

deploying a hardened interceptor drone in response to detection of the hostile drone;

tracking the hostile drone;

providing first targeting information to the hardened interceptor drone, the first targeting information configured to control a flight path of the hardened interceptor drone in a manner to intercept the hostile drone or to allow the hardened interceptor drone to target and track the hostile drone;

intercepting and colliding with the hostile drone by the hardened interceptor drone;

determining whether the hostile drone has been knocked out of the air;

repeating intercepting and colliding with the hostile drone by the hardened interceptor drone and determining whether the hostile drone has been knocked out of the air, until the hostile drone has been knocked out of the air;

20 deploying, concurrent with deployment of the hardened interceptor drone, a controller interceptor drone in response to detection of the control signals; and

providing second targeting information to the controller interceptor drone, the second targeting information configured to control a flight path of the controller interceptor drone in a manner to fly the controller interceptor drone to a location associated with the control signals.

20. The method of claim 19, further comprising locating, identifying and/or tracking an operator of a controller emitting the control signals, concurrent with the hardened interceptor drone intercepting and colliding with the hostile drone and/or thereafter.

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