

عنوان مقاله:

Sliding Mode Trajectory Tracking Control for a Quadrotor

محل انتشار:

شانزدهمین کنفرانس بین المللی انجمن هوافضای ایران (سال: 1395)

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خلاصه مقاله:

This paper presents tracking control design for a quadrotor based on sliding mode method. Quadrotor is a kind of flying robots, which has six degrees of freedom. Because of its under-actuated dynamic property, the controller can make quadrotor to track roll, pitch and yaw angles and

کلمات کلیدی:

Quadrotor - Sliding Mode Method - Controller - Tracking

لینک ثابت مقاله در پایگاه سیویلیکا:

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