

عنوان مقاله:

Cooperative Backstepping Control of Quadrotors via Sliding Mode Observer

محل انتشار:

نهمین کنفرانس ملی فرماندهی و کنترل ایران (سال: 1395)

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خلاصه مقاله:

This paper is mainly about backstepping control by running parallel sliding mode observer for a quadrotor Unmanned Ariel Vehicle. This sliding mode observer is filtered by a low pass filter to improve the performance of the observer. Forasmuch as filtering sliding mode outputs eliminates stimulated discontinuity of the sign function of observer,) smooth results achieved. This observer will estimate the disturbances and observe the velocities

کلمات کلیدی:

Backstepping control, Sliding mode observer, Quadrotor, Unmanned Ariel Vehicle

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