

عنوان مقاله:

Trajectory Tracking Control Problem of Multi-Agent UAV System

محل انتشار:

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خلاصه مقاله:

Formation problem of Unmanned Aerial Vehicles considered in this paper. The system linearized around hovering point and the controller based on error measurements from desired reference input has been designed and applied on single UAV and multiagent system as well. Tracking problem of UAV in order to reduce the error with the formation reference trajectory is the main control goal in this project, nevertheless the stability analyses and robustness examinations during the whole simulation shows that the system with designed controller is robust due to bounded uncertainty which is a validation to linearization because of VTOL flight model in UAVs

کلمات کلیدی:

UAV, VTOL, ROBUSTNESS, TRAJECTORY TRACKING, ERROR REDUCTION

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