Adaptive Neural Network Control of Quadrotor Unmanned Aerial Vehicle Transportation Systems

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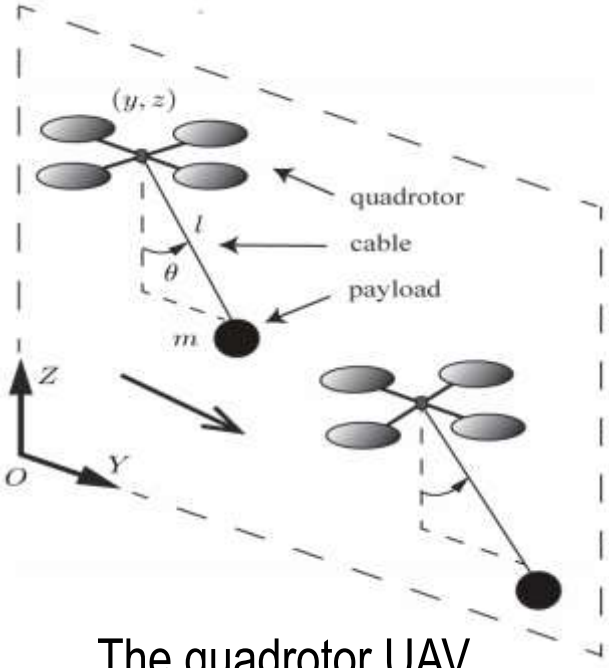
- An adaptive controller is proposed based on sliding manifolds and RBFNNs.
- RBFNNs are utilized to compensate for system uncertainties/disturbances.
- The stability of the system can be guaranteed by Lyapunov techniques.
- Simulation results show superior performance and robustness of the proposed adaptive NN controller



The quadrotor UAV transportation system