IEEE RCAR 2020 Digest
Observer-based Second Order Sliding Mode Control for TetheredQuadrotor Transportation

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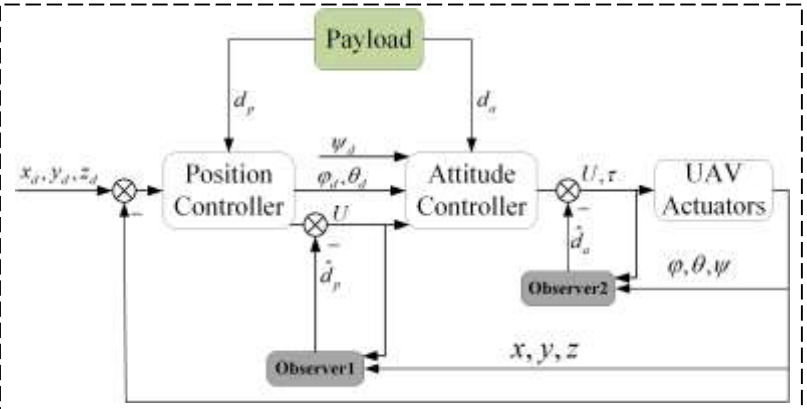
- Precise control: the disturbance can be ompensated in proposed controller via the signed observer.
- Comparative test verification: two different experiments were conducted by hovering test and circling test.



OBSOSMC structure diagram

- A double-loops observer-based second order sliding mode control scheme is proposed for tethered quadrotor transportation.