Trajectory Planning for Collaborative Transportation by Tethered Multi-UAVs

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- A multi-robot cooperative trajectory planning method with constraints is proposed.

- A Hybrid A* algorithm with cluster obstacle avoidance is used for path search.

- Some special rope constraints of UAV swarm flight are defined.

- The trajectory is optimized by nonlinear optimization with the problem of trajectory smoothing.

Collaborative Transportation
by Tethered Multi-UAVs