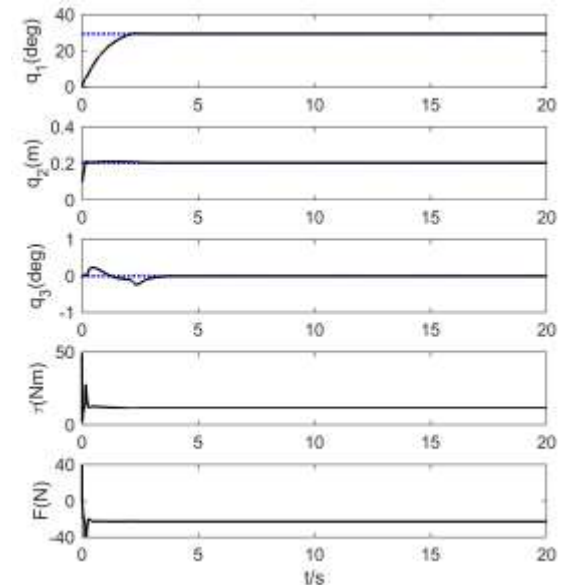


Stabilizing control for an offshore crane with unknown parameters

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- The Dynamic model of an offshore boom crane is established in the presence of ship roll motion
- A parameter independent coupling controller is proposed which combines the proportional derivative controller and the SMC, to regulate the cargo to desired positions.
- The closed-loop stability is analyzed and the effectiveness is verified via simulation results



Simulation results under regular waves