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Nonlinear control for collision-free navigation of UAV fleet

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摘要	<p>This paper presents the development of a cooperation scheme among unmanned aerial vehicle (UAV). Sliding mode control technique is used to guarantee that the set of robots can follow a reference trajectory and, in addition, will guarantee collision-free navigation of these autonomous vehicles. The analytical approach of the control strategy is shown, and the necessary conditions to guarantee the stability and governability of the multi-robot system are derived. The strategy and the derived conditions are tested using simulations, to demonstrate their effectiveness for collision-free navigation of an UAV fleet.</p>
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