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Autonomous Drone Simulation and Implementation, A Platform for Testing and Validating Quadrotor Control Algorithms

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Our work focused on building a platform designed to test and validate control, planning, and optimization algorithms for quadrotors, enabling simulation and deployment to benchmark drone-related algorithms. We successfully simulated minimum snap trajectory optimization with a geometric controller, and integrated image-based visual servoing for target detection.

Master

Laboratoire d'accueil

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