5 Conclusion

In this paper, the attitude control of the quadrotor system is controlled. Roll and pitch angles are controlled by PD and time-delayed control methods. Their control performances are compared empirically. The time-delayed control method shows the outperformed control performance over the PD control method, especially when the disturbance is applied to the system. The time-delayed control method can be applied to the hovering control of the quadrotor system in the future.

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