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GADJAH MADA

Hover and Auto-Landing Control on Quadcopter Using Proportional Derivative Control With Disturbance

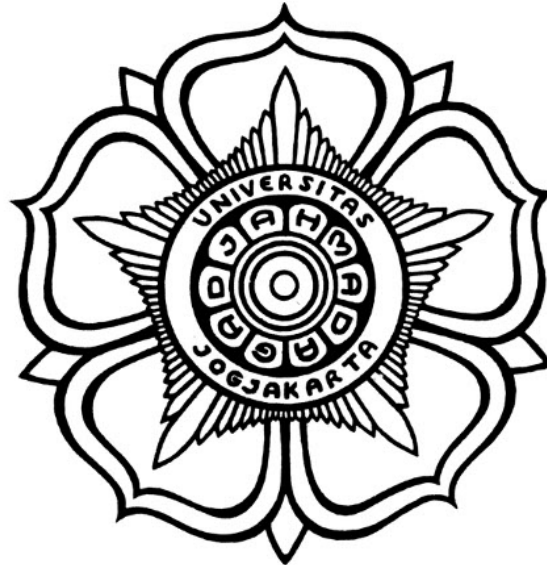
Observer Based Disturbance Rejection

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HOVER AND AUTO-LANDING CONTROL ON QUADCOPTER USING PROPORTIONAL DERIVATIVE CONTROL WITH DISTURBANCE OBSERVER BASED DISTURBANCE REJECTION

FINAL PROJECT REPORT



**THE SUSTAINABLE DEVELOPMENT GOALS
Industry, Innovation and Infrastructure
Affordable and Clean Energy
Climate Action**

Written by:

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**STUDY PROGRAM BACHELOR IN ELECTRICAL ENGINEERING
DEPARTMENT OF ELECTRICAL AND INFORMATION
ENGINEERING
FACULTY OF ENGINEERING UNIVERSITAS GADJAH MADA
YOGYAKARTA
2025**

HALAMAN PENGESAHAN

**HOVER AND AUTO-LANDING CONTROL ON QUADCOPTER USING
PROPORTIONAL DERIVATIVE CONTROL WITH DISTURBANCE OBSERVER
BASED DISTURBANCE REJECTION**

SKRIPSI

Diajukan sebagai Salah Satu Syarat untuk Memperoleh

Gelar Sarjana Teknik

pada Departemen Teknik Elektro dan Teknologi Informasi Fakultas Teknik

Universitas Gadjah Mada

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