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## Path Planning Algorithm based on Arnold Cat Map for Surveillance UAVs

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and more threats coming from both ground and air. In charge with surveilling a specified 3D sector must y entities. In our view, the chaotic dynamics can be n was not exploited until now by researchers in the 3D dversarial conditions by proposing a proficient he exact location of the volume under surveillance ard resources, in an efficient manner. The method is quadcopter.

[d's cat map](#); [volume surveillance](#)

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