

Radio Flyers

EE 41440

04 April 2012

Minutes 04-04-12

PWM output works:

Board:

- Program it to see if it works
- Keep track of changes

Controls:

- Look up data fusion for gyro and accelerometer
- Use that data to keep the quad-rotor at desired position
- Control algorithm will compare that desired with the actual
- PID will generate error

For next week

- Be able to talk to each individual sensor to see if it makes sense
- Sensors may sample faster than control algorithm. (may be able to do a moving average on sensor readings)
- Main will compare desired position to actual position
- PI controller is more critical than PD controller