

Controller

Mixer

Actuators

th

m_x

m_y

m_z

$$th_1 = th$$

$$th_2 = th$$

$$cs_1 = k_{cs}(m_x - m_z)$$

$$cs_2 = k_{cs}(-m_y - m_z)$$

$$cs_3 = k_{cs}(-m_x - m_z)$$

$$cs_4 = k_{cs}(m_y - m_z)$$

th_1

th_2

cs_1

cs_2

cs_3

cs_4

Motors

Servomotors