# Readed documents

Threading: <https://realpython.com/intro-to-python-threading/?fbclid=IwAR2TSUXQbtl00Vf-eHq4HlFVi5VhU9f8ZzhJrKzQ5alHuQK4jEHGKHXjMSU>

Pi cam: <https://picamera.readthedocs.io/en/latest/recipes2.html#rapid-capture-and-streaming>

Pi to Pix: <https://ardupilot.org/dev/docs/raspberry-pi-via-mavlink.html>

Mavlink: <https://mavlink.io/en/messages/common.html>

Pixhawk6 layout: <https://docs.holybro.com/autopilot/pixhawk-6c/pixhawk-6c-ports>

Install Pi to Pixhawk: <https://ardupilot.org/dev/docs/raspberry-pi-via-mavlink.html>

# Report:

## Week 39:

The task that was given to the student was to establish the connection between the ground control station, the sever, and the flight controller through internet connection as well as evaluating the delay between them. At the beginning the student identified that there were two set up options to accomplish the task, all have their advantages and disadvantages:

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| --- |
| Configuration 1: Setting the sever on the drone, separrate from the ground control station |
| Configuration 2: Setting the sever and the ground control station as one |

|  |  |  |
| --- | --- | --- |
|  | Advandtages | Disadvantages |
| Configuration 1 | There will be |  |
| Configuration 2 |  |  |