

Autonomous Quadrotor Landing on a Moving Platform

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Introduction

Our goal is to autonomously land a quadrotor onto a moving platform. In this interim-report we will discuss our efforts so far, and any preliminary results we may have. So far we have spent a considerable amount of effort getting different components of the project working. In this report we will be discussing progress in both hardware and software aspects of the project, specifically:

- Quadrotor Setup and Onboard Computer
- Camera

Hardware

For the hardware, we have chosen to reuse equipment that is readily available to us in the Wave Lab. For the quadrotor we are using



Figure 1: DJI F450 with Pixhawk v1.5

Software

Pixhawk Firmware

Simulator

AprilTag