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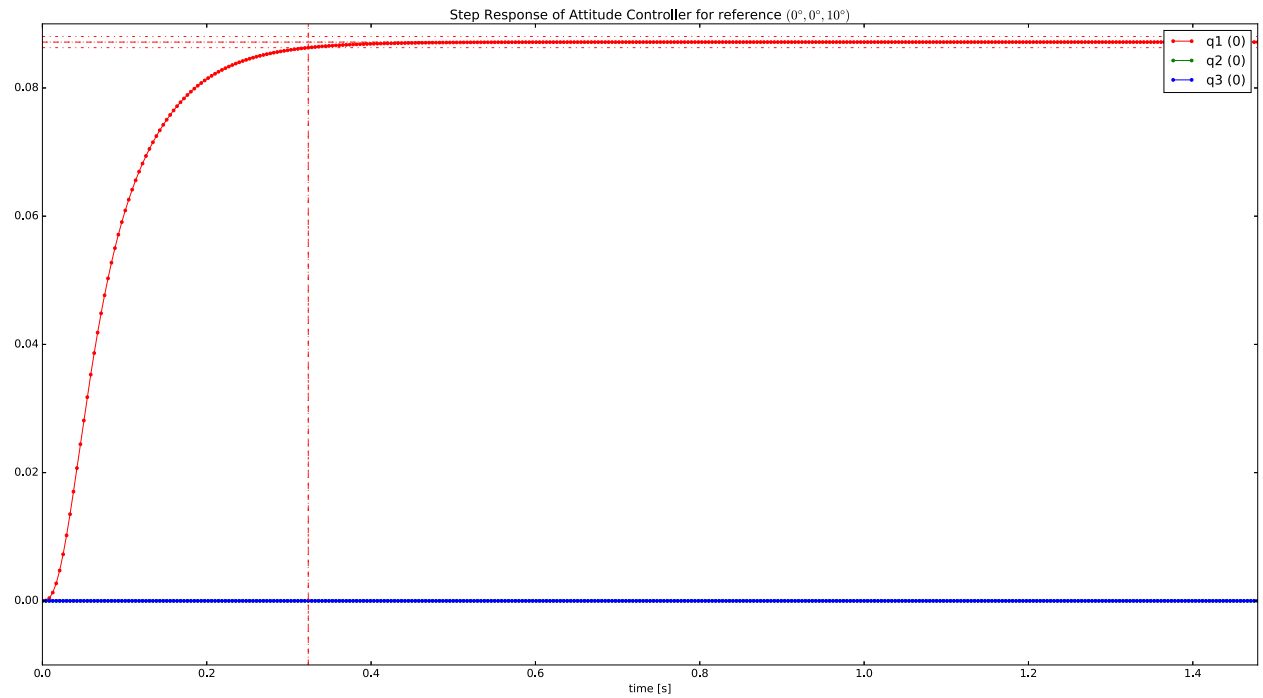
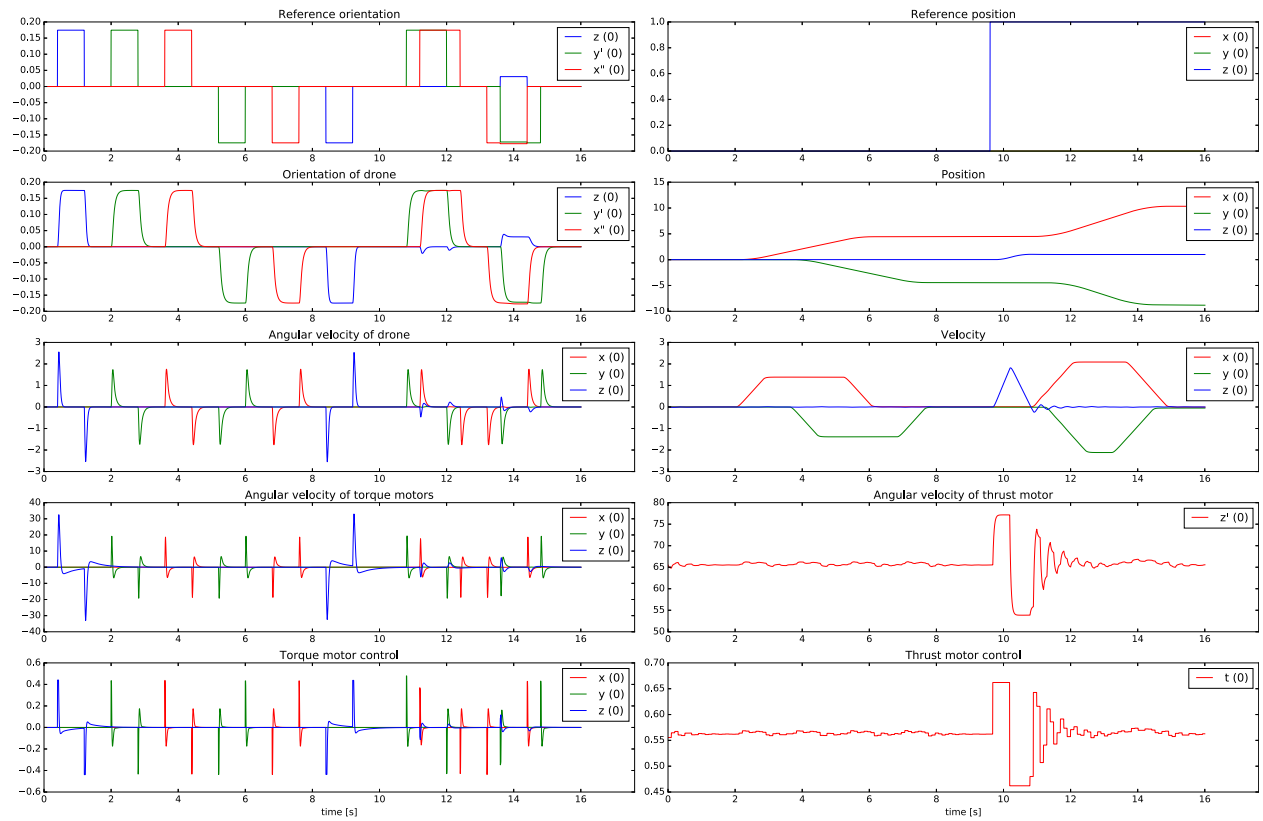
Model

- $\text{\boldsymbol{q}}$ is the orientation of the drone, expressed as a unit quaternion.
- ω is the angular velocity of the drone.
- n is the speed of the torque motors.

Controller

1. Bias rejection attitude controller
2. Integral controller attitude controller
3. Flippen observer als yaw > 90°
4. SSH is traag
5. SSH fingerprint verandert heel de tijd
6. PWM limits: multiple defines
7. Router board bevestigen op de drone
8. Calibratie wanneer thrust geclamped wordt
9. Als de controller wegvalt, moet de drone stoppen!

1. ✓ Bias rejection attitude controller
2. ✓ Clamp thrust to 80%
3. ✓ Vliegen RC attitude + filmpje
4. ✓ Vliegen met altitude + filmpje
5. ✓ Schema controllers/observers afwerken
6. ✓ Montage GA
7. ✓ Blender animation
8. Keep q_0 positive (slide 135)
9. ✓ Observer reset als thrust 0
10. Mousse IMU
11. When switching from altitude to attitude, gradually change thrust



Processing math: 100%

