

January 18, 2016
Meeting 1 of Spring 2016

Quadcopter Project Improvements and Goals

- A maximum of 30 minutes will be spent on coding puzzles each meeting.
- Rotate puzzles and send email with instructions before every meeting to save time.
- Ilya will also take up responsibility for every other task so he can motivate other team members.
- Attendance and commitment is important. Let Ilya know if you can't make it.
- Show up on time.
- Tutorials will be related to the project. If they are not, team members will vote on whether they want to learn that certain topic or not.
- Tutorials should be documented.
- Interview preparation will be in place of the coding puzzles occasionally.
- It would be nice to have a documented GitHub tutorial.
- Quadcopter tutorial should include specs (how much it can carry, battery life, forum research), software only if necessary, and what we can do.
- Goals for this semester:
 - Stable hovering
 - Determine if we need a camera
 - Testing
 - Manipulating inputs/outputs
 - Be better at programming and disassembling code, gain better understanding of software

Coding Puzzle

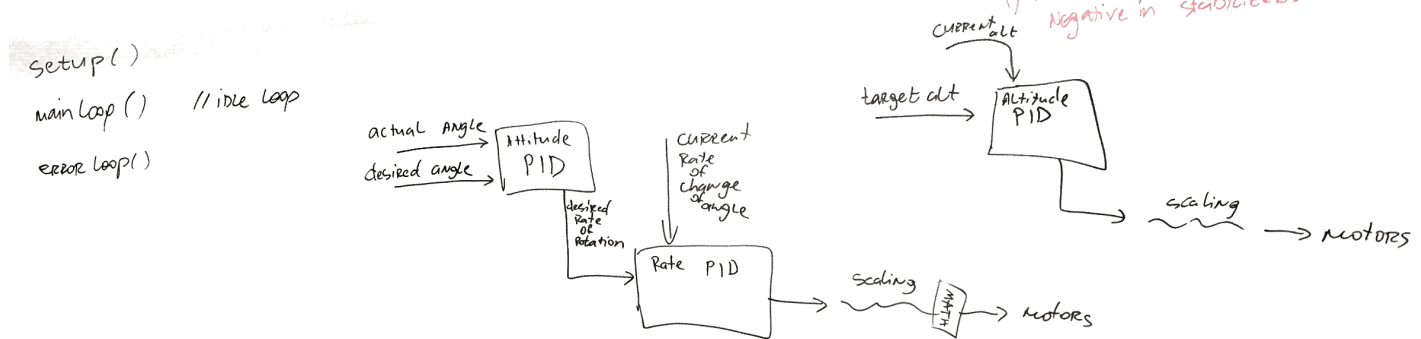
WAP to swap two data values without using a temporary variable.

Program:

```
int main()
{
    int a = 5;
    int b = 3;
    swap(&a, &b);
    printf("%d %d \n", a, b);
}

void swap(int *a, int *b)
{
    *a = *a^*b; // a = 0000 0110, b = 0000 0011
    *b = *a^*b; // a = 0000 0110, b = 0000 0101
    *a = *a^*b; // a = 0000 0011, b = 0000 0101
}
```

Notes



Tasks

- Find out why `eulerYawDesired` is negative in `stabilizer.c` (*Mason and Diva*)
- Research on basic concepts of quad before quad tutorial (*Everyone*)
- Logging (*Pat and Mason*)
 - Find a good way to log yaw, pitch, roll (desired)
- Find more ways to capture desired pitch/yaw/roll (*Pat and Diva*)
 - Research on the web
 - Search for something like “autonomous hovering algorithms”
- Figure out how to determine if the quad is stable. (*Everyone*)

Next Meeting

- Get Wangi up to speed
- Tasks update(s)
- Talk about task 1 and 2
- Plug in rates of change