PRU

Sensors

Accel-z
Altitude

Kalman
Filter

$\dfrac{\text{Cleaned}}{\text{Altitude}}$
Vel

Surface
model
FIT

Drag
Coef
(CD)

ADS Plan
IF CD=X: Rotate $X^\circ$
⋮

$Y^\circ \to \theta$

$\theta$ → PRU

PWM

FINS!!

∩S∙

PRU1
Sensor

PRU2
Actuator

KF

Logger

ADS

PRU

## Sensor

lg : Logger

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altimeterSetup( )
imuSetup( )

---

init( )
    GPIOConfig( ) ← JUST LISTEN

        imu
        alt

## Actuator

lg : Logger

---

init( ) ← setup Pins
Pwm( )

## ADS

KF : Kalman Filter
lg : Logger

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SurfaceModelFit( )
ADSPlan( )
update : RocketState( )
Percentage2Angle( )

---

readSensor( )
actuatorOut( )
run( )

Don't Peek!

update member
vars
    ← alt
    ← a-z