Week9

a. We marked forward direction with tape and tested the ground flight. However, our yaw controller was not good enough to make us move our quadrotor in a straight line.
We calibrated our motors on Sunday. Because when set four motors to same PWM value, some motors turned out to be stronger than others.

b. We plan to tune our PI yaw controller first, for straight control. Then we will tune our PID roll/pitch controller again for better control.
Our quadrotor cannot move straightly may because of bad PI yaw control, or the battery connector may cause problem when calibrating.
We need to realize hover flight, and that is also related to yaw control.

c. – Felix-kim 50%
   - Mengjiao Hong 50%
   We learn and do everything together, and contribute evenly to our job.

d. Attached codes