Follow Color IV

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Tello Driver

- **Cmd Rate:** 20 Hz
- **Data Rate**: 10 Hz
- **Video Rate**: 30~35 FPS
- **Frame:** MAV_FRAME_LOCAL_FLU (#21)
- **Mask:** tres válidas: 3064 (posición), 1991 (velocidad), 1987 (despegue, cambio en altura)
- **Control Policy**: Vel > Pos

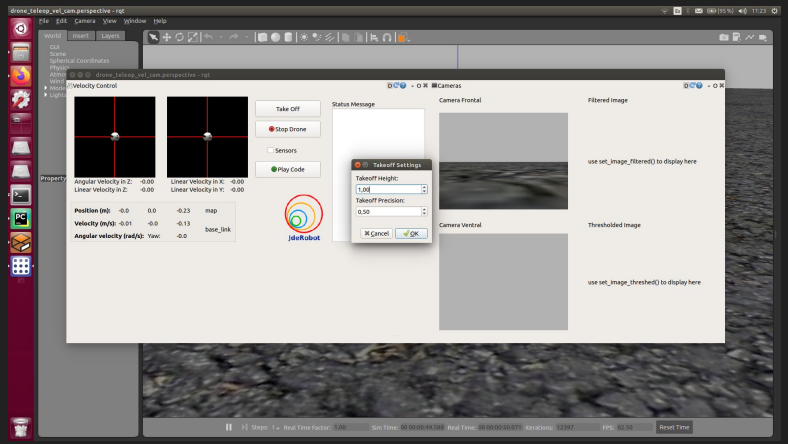
RQT Drone Teleop

Takeoff Menu

RQT launch

```xml
<?xml version="1.0"?>
<launch>
    <arg name="perspective" default="$(find rqt_drone_teleop)/perspectives/drone_teleop_vel_cam.perspective"/>
    <arg name="height" default="3"/>
    <arg name="precision" default="0.05"/>

    <param name="rqt_drone_teleop/height" type="double" value="$(arg height)"/>
    <param name="rqt_drone_teleop/precision" type="double" value="$(arg precision)"/>
    <node name="rqt_gui" pkg="rqt_gui" type="rqt_gui" respawn="false" output="screen" args="--perspective-file $(arg perspective)"/>
</launch>
```



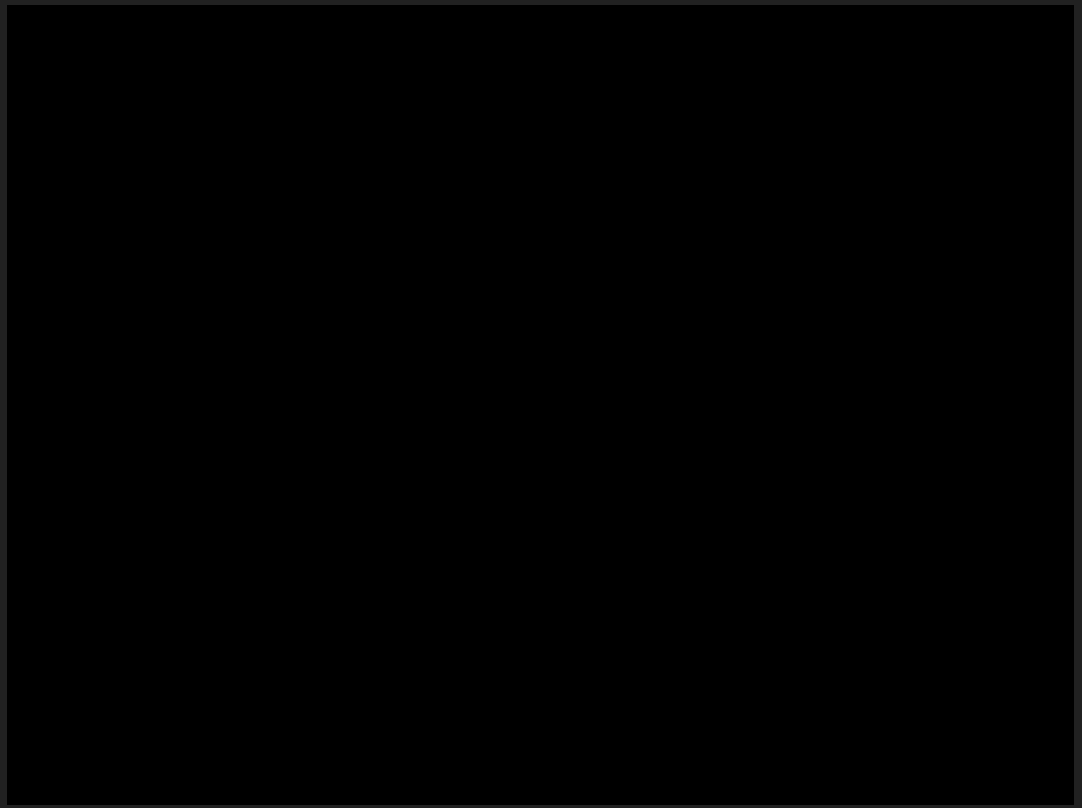

```xml
<?xml version="1.0"?>
<launch>
    <!--    Drone model param    -->
    <arg name="drone_model" default="tello"/>
    <param name="drone_model" type="str" value="$(arg drone_model)" />

    <arg name="perspective" default="$(find rqt_drone_teleop)/perspectives/drone_teleop_vel_cam.perspective"/>
    <arg name="height" value="1"/>
    <arg name="precision" value="0.5"/>

    <node name="tello_driver_node" pkg="tello_driver" type="tello_driver_node.py" output="screen"/>
    <node pkg="drone_wrapper" type="drone_wrapper_class.py" name="drone_wrapper_node" output="screen"/>
    <include file="$(find rqt_drone_teleop)/launch/rqt_drone_teleop.launch">
        <arg name="perspective" value="$(arg perspective)"/>
        <arg name="height" value="$(arg height)"/>
        <arg name="precision" value="$(arg precision)"/>
    </include>
</launch>
```

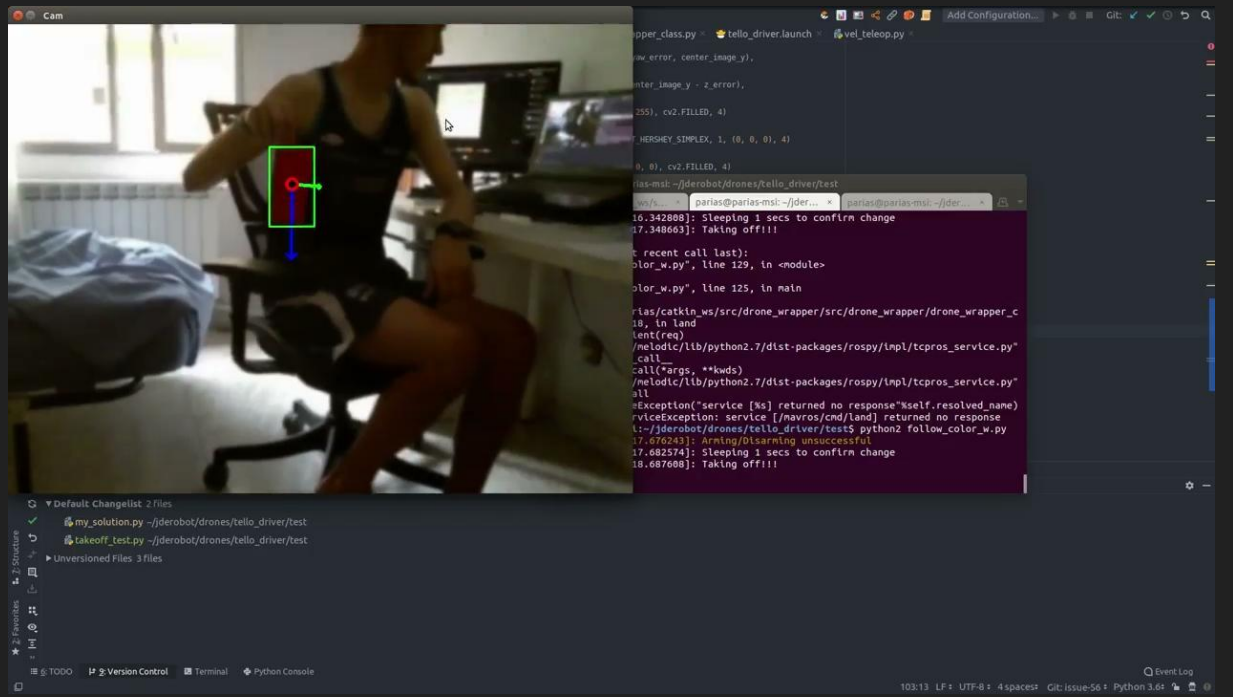
Follow Color - Yaw, Vz, Vx

- Yaw:
  - P=0.002, I=0, D=0.001
- Vz:
  - P=0.0015, I=0, D=0
- Vx:
  - P=0.2, I=0, D=0.002



Follow Color WRP - Yaw, Vz, Vx

- Yaw:
  - P=0.002, I=0, D=0.001
- Vz:
  - P=0.0015, I=0, D=0
- Vx:
  - P=0.2, I=0, D=0.002



Follow Color RQT - Yaw, Vz, Vx

- Yaw:
  - P=0.002, I=0, D=0.001
- Vz:
  - P=0.0015, I=0, D=0
- Vx:
  - P=0.2, I=0, D=0.002