1. Quadplane in hovering mode

Switch in manual mode, target altitude at 150cm, throttle stick at zero,

* 1. Telemetry

**Build with TestGains and disableEmergencyLanding flags activated (means that we are in stabilized mode)**

Using throttle stick, check that telemetry throttle output reacts correctly in real time

* 1. Motor control

**Build with TestGains and disableEmergencyLanding flags activated (means that we are in stabilized mode)**

Set throttle stick at around ¼. Then using the roll and pitch stick, check the motor response :

* Roll order to the right : right motors should slow down, left motors should accelerate
* Forward pitch order : front engines should slow down, rear engines should accelerate
  1. Altitude control

**Build with TestGains,TestAltitude and disableEmergencyLanding flags activated (means that we are in stabilized mode)**

* + 1. Check control of target altitude

Using telemetry, check that the Tx right potentiometer correctly commands the target altitude. Check that the expected minimum and maximum target altitudes are obtained

* + 1. Apply the take-off procedure until stabilized altitude control is engaged. Then verify that :

1. When plane altitude is equal to target altitude, the throttle should be

throttle\_offset throttle\_offset = 2\*SERVORANGE\*AircraftMass / (100 \* MaxThrust)

For AircraftMass = 1250g ; MaxThrust = 40N ; throttle = 625

1. Modify the target altitude to obtain target\_altitude – plane\_altitude = 50cm. Then check that throttle = throttle\_offset + 2 \* AircraftMass / (100 \* MaxThrust) \* zkp \* vzkp \* acczkp \* 50

For zkp = 9 ; vzkp = 4.8 ; acczkp = 0.6, then throttle = throttle\_offset + 810 = 1635

* + 1. Lidar failure

Check that sonar altitude is close to lidar altitude.

Mask the lidar with your hand. Check that the altitude is now determined by the sonar and that the altitude and the throttle behave smoothly during the transition.

* 1. Functional test

**Build only with the disableEmergencyLanding flag**

* + 1. Engine safe initialization

**In manual mode :**

check that engines are off when throttle stick is at zero

set throttle stick to a value greater than 20%. Check that roll and pitch stabilization works as described in section 1.2

check that flight phase is 0

* + 1. Standard flight

**Switch to stabilized mode :**

Check that engines run at 20%

Move uav at a height of 1.5m. Check that reliable altitude measurement switches to 1. Check that flight phase switches from 0 to 1.

Move uav to a height smaller than 80cm. Check that reliable altitude measurement switches to 0. Check that flight phase switches from 1 to 2. Check that the engines slow down until they stop. Check that flight phase switches from 2 to 0.

* + 1. Manual override

**Test 1 :**

Switch to stabilized mode :

Check that engines run at 20%

Switch to manual mode. Check that the engines respond to throttle stick

**Test 2 :**

Switch to stabilized mode :

Move uav at a height of 1.5m. Check that reliable altitude measurement switches to 1. Check that flight phase switches from 0 to 1.

Switch to manual mode. Check that the engines respond to throttle stick

**Test 3 :**

Switch to stabilized mode :

Move uav at a height of 1.5m. Then move uav to a height smaller than 80cm. Check that flight phase has switched to 2. Switch to manual mode. Check that the engines respond to throttle stick

* + 1. Stabilized mode after manual override

Switch to stabilized mode :  
Move uav at a height of 1.5m. Check that reliable altitude measurement switches to 1. Check that flight phase switches from 0 to 1.  
Switch to manual mode.  
Then switch to stabilized mode. Check that integral terms in altitude control PIDs have been resetted to zero.

* 1. Emergency landing

**Build only with the testEmergencyLanding flag**

testEmergencyLanding sets max altitude to 1.7m

Either manual, stabilized or GPS mode is engaged, the failsafe mode should be activated in the following cases :

|  |  |  |  |
| --- | --- | --- | --- |
|  | Low battery | Radio off | Max altitude exceeded |
| Test 1 | 1 | 0 | 0 |
| Test 2 | 0 | 1 | 0 |
| Test 3 | 1 | 1 | 0 |
| Test 4 | 0 | 0 | 1 |

* 1. Altitude sensor failure

**Build with the disableEmergencyLanding**

* 1. GPS mode

**Build with the disableEmergencyLanding and test GPSPositioning flags**