



Flight

Ⓜ M600Flight

Ⓜ GCS

π CLIMB_LIFT: real

π DELAY_DISARM: int

π HOME: Position

✕ h: real, cmd: NavCommand, vnav: VNavOutput, wp: Position

✕ start: Position, gotStart: boolean = false

ⓘ M600FlightEvents

ⓘ M600TelemetryEvents

ⓘ GCSControlEvents

ⓘ FlightPlanningEvents

ⓘ VNavSubscriber



Connect

fcControlAuth/uavStatus!AircraftStatus::Connected

Waiting

waypoint?wp

Waypoint

entry if not gotStart then start = wp; gotStart = true end; fcWaypointCall(wp)

Climbing

entry wp = HOME; wp.alt = wp.alt+CLIMB_LIFT; fcWaypointCall(wp)

TakingOff

entry fcTakeoffCall()

navCommand?cmd

fcWaypointFinishedMission/uavStatus!AircraftStatus::AtHome

Relative

entry fcMoveRelativeCall(vnav.rpos)

[gotStart]

BackToStart

entry fcWaypointCall(start)

fcWaypointFinishedMission

Landing

entry fcLandCall()

F

fcTakeoffRet

fcGoHomeRet

fcLandRet

fcControlAuth

fcWaypointFinishedMission

fcMoveRelativeRet