

# Quadcopter Project

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August 27, 2015

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## 1 Specifications

The quadcopter will be designed to fulfill the following functionalities:

- Self stabilization.
- Manual pilot through RF controller.
- FPV with On-Screen telemetry.
- Headfree mode.
- GPS:
  - Hold position.
  - Back-home.
  - Waypoints.
- WiFi connection to Android smartphone.

## 2 Hardware

- **Frame.** X525 V3.
- **Flight controller.** Crius All-in-one Pro v2.0, featuring:
  - Atmega 2560.
  - MPU-6050 (3-axis accelerometer + 3-axis gyro) IMU with Motion Processing Unit.
  - HMC5883L 3-axis magnetometer
  - MS5611-01BA03 high precision barometer.
- **GPS.** Ublox NEO-6 v3.0, included with the flight controller.
- **Motors.** Turnigy D2836/8 1100KV
- **ESCs.** TURNIGY Plush 30amp Speed Controller
- **Propellers.** Slow Fly Electric Prop 1045
- **Remote controller.** HK6s 2.4 GHz FHSS 6CH Tx & Rx
- **FPV kit.** Quanam Complete FPV Bundle Set
- **On-Screen Display (OSD) module.** MinimOSD
- **WiFi module.** ESP8266.

- **Bluetooth module.** HC-05.
- **Battery.** ZIPPY Compact 3700mAh 3S 25C
- **Power distribution board.** Hobby King Quadcopter Power Distribution Board
- **Camera.** Mobius.

## 3 System Overview

## 4 Control

### 4.1 Low-level

### 4.2 High-level

## 5 Communications

### 5.1 Protocol

- Raw sensor data
  - Accelerometer
  - Gyro
  - Magnetometer
  - Barometer
  - Temperature
- GPS information
- Computed quaternion
- PID controller
- RC sticks