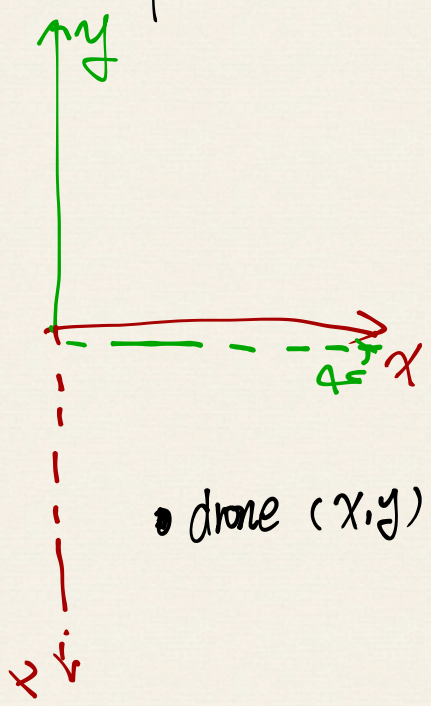
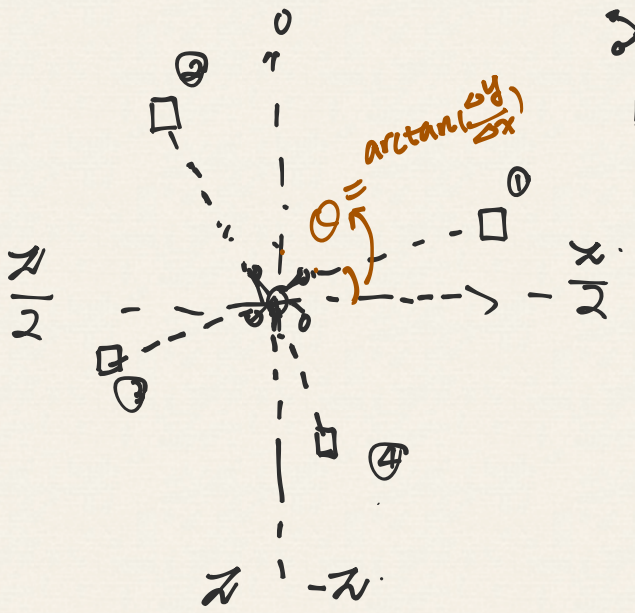
- Coordinates for obstacles: ——
  - - · for the drone: - - - - .



Thus drone coordinates in "obstacle" space:

$x_{new} = data.y$

$y_{new} = -data.x$



: drone

□: obstacles

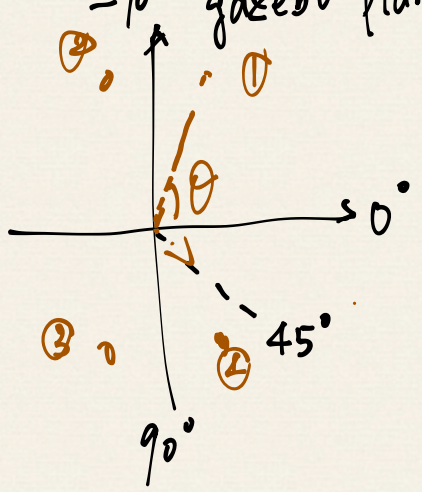
① $-\frac{\pi}{2}+\theta$

② $\frac{\pi}{2}+\theta$

③ $\frac{\pi}{2}+\theta$

④ $-\frac{\pi}{2}+\theta$

- in turn-drone, the definition of yaw is:



dest	direction (absolute)
①	$-\theta$
②	$\pi-\theta$
③	$\pi-\theta$
④	$-\theta$

Note: $\theta = \arctan(\frac{\Delta y}{\Delta x})$