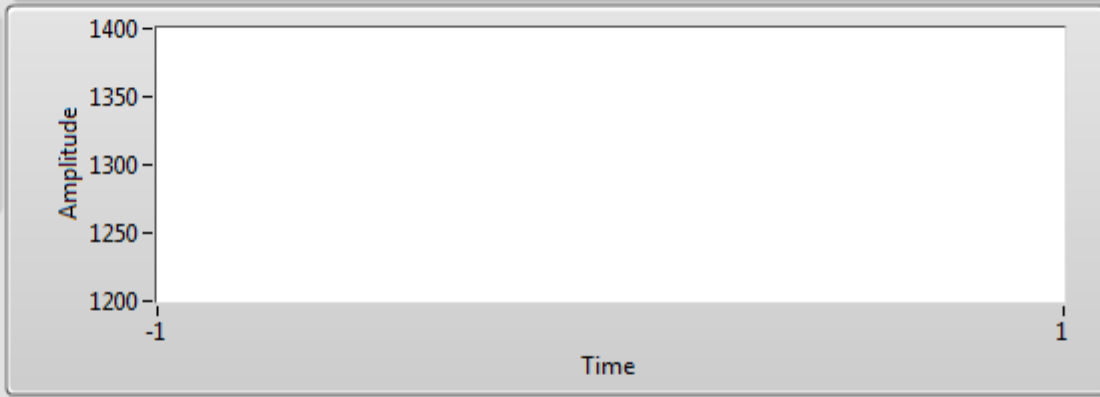
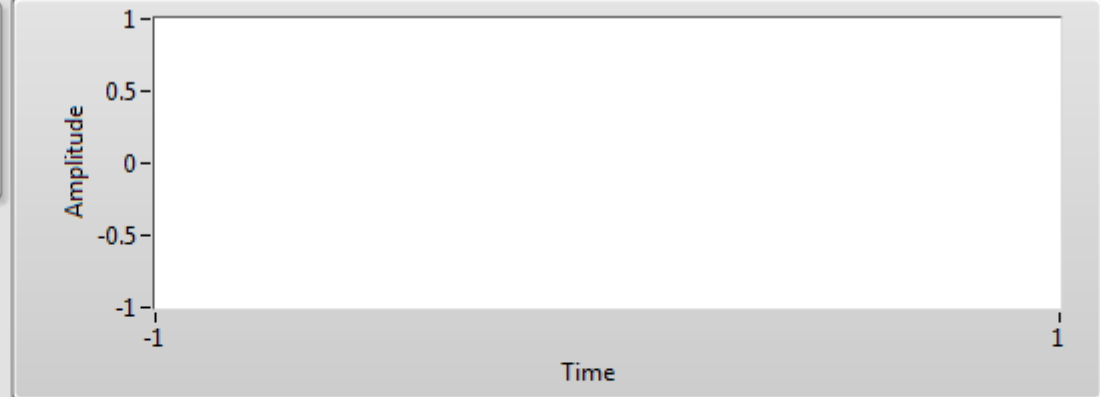


- SetPoint
- Pitch
- Roll
- Yaw

Yaw 2
0

- ESC1
- ESC2
- ESC3
- ESC4



START

StartSimulation

StopSimu

StopSimulation

Stop Motors

StopMotors

Reset

OK

alpha

1

beta

1

SP Frec

0

SP Amp

0

PWM4

A/PWM2

PWM2

B/PWM2

PWM1

A/PWM1

PWM3

B/PWM1

AnPitch	RaPitch	AnRoll	RaRoll	AnYaw	RaYaw
Kp 0	Kp 0	Kp 0	Kp 0	Kp 0	Kp 0
Ki 0	Ki 0	Ki 0	Ki 0	Ki 0	Ki 0
Kd 0	Kd 0	Kd 0	Kd 0	Kd 0	Kd 0

Throttle

esc4

esc2

esc3

esc1

Pitch

PID_Angle

PID_Angle
-0.475583

PID_Rate

Rate_Error
0.0735373

Roll

PID_Angle

PID_Angle
-0

PID_Rate

Rate_Error
-0

Yaw

PID_Angle

PID_Angle
-0

PID_Rate

Rate_Error
0