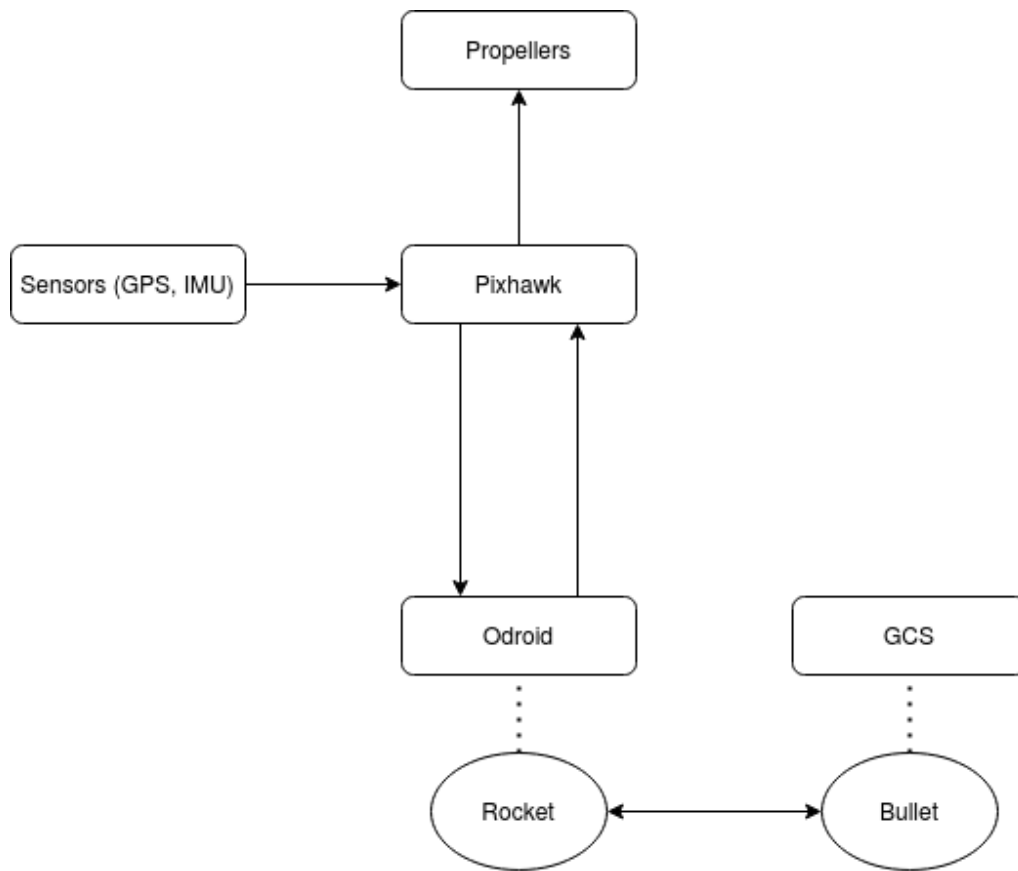


Flow of Data



- Pixhawk receives information from sensors (GPS, IMU) about the state and attitude of the aircraft to perform state estimation
- It is also an autopilot that can take waypoints from Odroid and give required commands to control flight path
- Odroid gets the flight sensor data and the state (position and attitude) of the quadcopter from Pixhawk
- The GCS and onboard computer Odroid are connected by a wireless network created by Rocket M5 and Bullet
- The codes on Odroid can be accessed and run on GCU through the wireless network