**ENCE361 – Helicopter Assignment 2015**

The aim for each group is to produce a program to control a model helicopter.

The Stellaris EVK is to be programmed with a small real-time kernel and interrupt-driven control program designed to control the lift off, hover, heading while hovering, and landing a small model helicopter mounted on a telescopic post. The power to two motors, one for the main rotor and the other for the stabilising tail rotor, is to be controlled by pulse width modulated (PWM) outputs. Feedback to the Stellaris EVK is available in the form of altitude and yaw signals.