AAH\_TESTCASE = 0-9

High\_control\_law.cpp

Flight\_control()

In autopilot, continuously updates timesteps (Not in manual mode)

Only works in autopilot

Man\_xx\_in: manual control

Last\_man\_xx\_in: last control before autopilot

AAH\_SET\_YAW: (FOR TEST CASE 6, sets the exact yaw you want (-pi – pi)

ROTANGLE: degrees we want to turn when we hit (0,0,0)

High\_params.c: converts from QGroundcontrol to c++

Low\_params.c: converts from QGroundcontrol to c++

CLOSENESS\_THR: meter distance from waypoint to change turn

FOllowline mode1 = Durand, 2 = lake lag