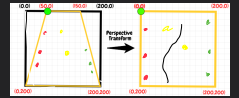


Problem

Behaviour

Perspective View

$$\begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1/f & 0 \end{bmatrix} \begin{bmatrix} x \\ y \\ z \end{bmatrix} = \begin{bmatrix} x \\ y \\ z/f \end{bmatrix} \Rightarrow \begin{pmatrix} f x_z \\ f y_z \\ z \end{pmatrix} \Rightarrow (u, v)$$



2. KISIM

2

Üst gözet



30%

1. KISIM

A*

29f

175

y

x

100%

30m

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Rotasyon Motoru

cos θ - sin θ 0

sin θ cos θ 0

0 0 1

0 0 1

0 0 1

0 0 1

0 0 1

0 0 1

0 0 1

0 0 1

0 0 1

0 0 1

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0 0 1

0 0 1

$$\vec{p} = [x \ y \ \theta]^T$$

x

θ -> Heading

t = t₁ - t₂

USU Kontrol

MPC

T200

PWM setpoint

Heading setpoint

PID

ESC

ESC

Brushless Motor

Brushless Motor

Brushless Motor

Brushless Motor

Brushless Motor

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PID Anon Heading Setpoint

