



- ① Control Problem
 - ↳ input: desired angle θ .
 - ↳ output: direction of motor y . (Voltage) → motor speed → $\dot{\theta} \left(\frac{d\theta}{dt} \right)$.
 - ↳ current state: current angle θ .

RPi
Gyroscope on
 - ② Getting GPS coord. from drone to RPi.
 - ↳ MAVSDK
 - ↳ compare w/ GPS coord. on antenna
 - ③ Converting GPS ⇒ vector
 ↓
 desired angle.
- GPS coords → drone → antenna
- 0.5 Have a controller for Motor
- CAD

