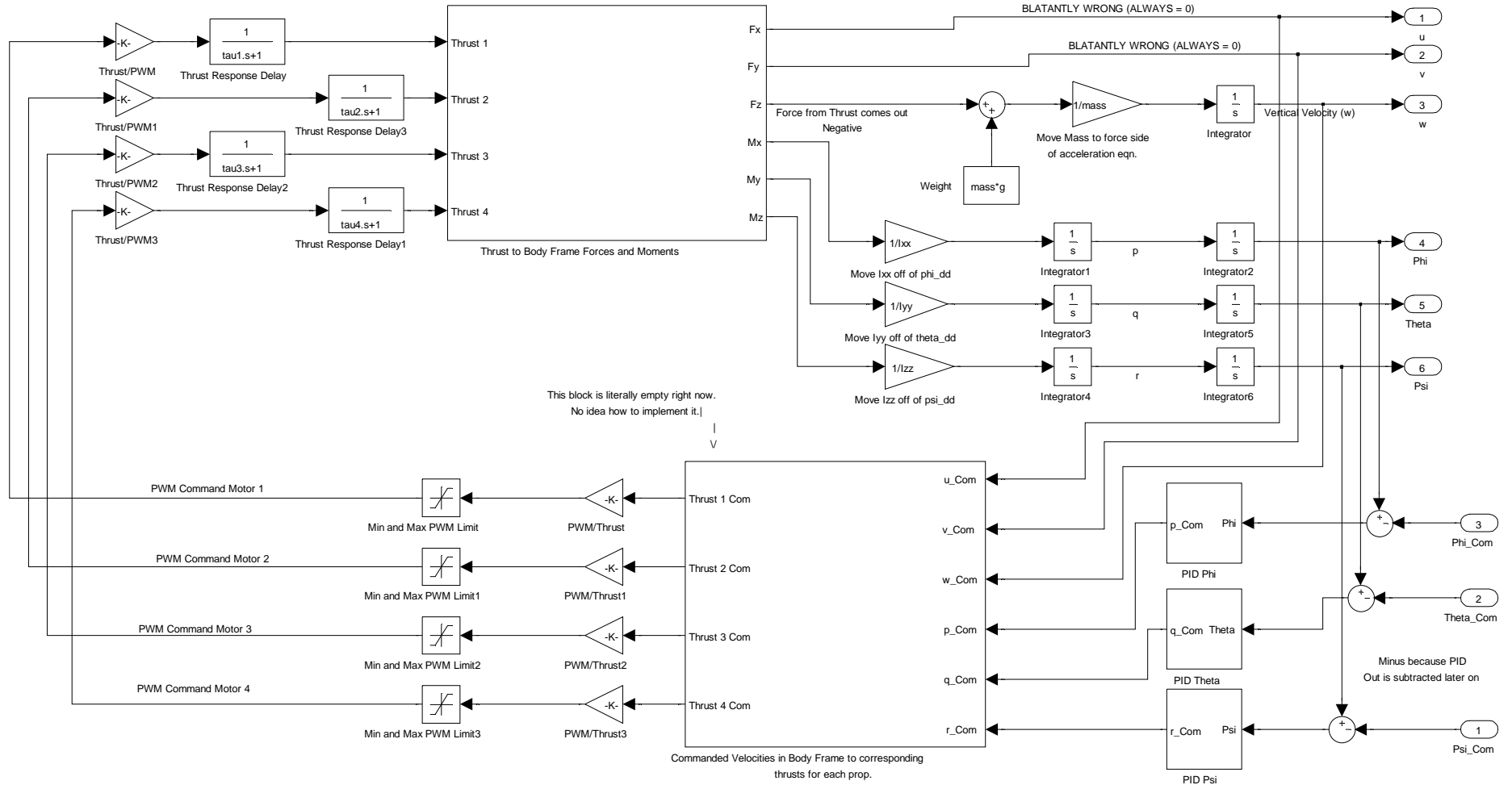
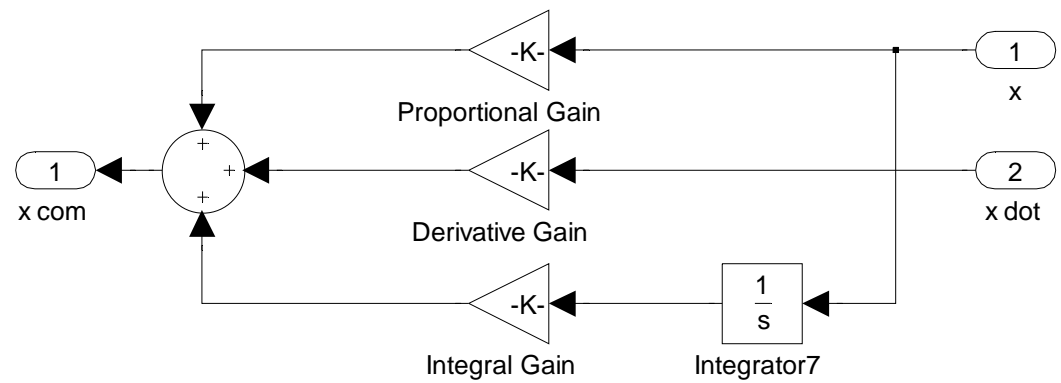


Alternate PID
 for use with a pure rate signal
 instead of taking a derivative

Storque UAV Control Model Simulation Version 1
 Simplified 2D physics (No 3D effects), Linear, Assumes gravity's direction changes with
 the body frame (And so is always in the +Z direction)

Also, the (u,v,w,p,q,r) Commands -> Thrust Commands Block is not implemented.
 Not entirely sure how to do this yet. If we fix the Thrust->Body Frame block so that
 Fx and Fy aren't broken and find that the necessary function mapping motor thrust to motor
 moment (ie: $M_x = F(T_x)$) is linear then I know how to do it...but other than that I'm not sure.





1 <
Thrust 1 Com

2 <
Thrust 2 Com

3 <
Thrust 3 Com

4 <
Thrust 4 Com

< 1
u_Com

< 2
v_Com

< 3
w_Com

< 4
p_Com

< 5
q_Com

< 6
r_Com

