getStatusMotorA decreaseMotorA | Motors increaseMotorA setMotors(thrustVector) setMotor(a,b,c,d) hoverNow Motor Controller(100hz Interrupt) 2. thrustVector(x,y,z) calculateCounteringThrustVector(x degree,y degree,z degree) 3. motorController.setMotor(thurstVector) getOrientation 1.1 Gyro 1.1.1 getZ hoverNow 1.1.3 getY 1.1.2 getX landNow takeOff flyTo Flight VTOL AMAV HIGH LEVEL CLASS DIAGRAM **AI CORE** Only the public functions are shown. Private members and functions are ommited Sensors Communication | PIR e getStatus Short Range IR e getDistance e updateDistance(100hz Interrupt) Gyro -Long Range Sonar/IR getDistance Accelerometers getY updateGyro(100hz Interrupt) getX getZ toPC toPayload - Serial getZ Serial getY getX updateAccel(100hz Interrupt) Subtopic 4 out getSsignalStrength getCommStatus out getSsignalStrength getCommStatus ⊇. updateDistance(100hz Interrupt)