Skripsie Title

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Report submitted in partial fulfilment of the requirements of the module Project (E) 448 for the degree Baccalaureus in Engineering in the Department of Electrical and Electronic Engineering at the University of Stellenbosch

Supervisor: N Surname

November 2018

Acknowledgements

Lorem ipsum

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Skripsie Title

Author Name

Abstract

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Contents

List of Figures

List of Tables

Nomenclature

List of Abbreviations

BBB Bla Bla Bla

List of Symbols

α the angle between mass ang gravity vector

Chapter 1

Introduction

1.1 Background

Bla Bla Bla (BBB)

1.2 Project Objectives

The aim of the project is ....

1. Item 1
2. Item 2

1.3 Literature Review

Someone else did something else [1].

1.4 Methodology

1.5 Report Outline

Chapter 2

Vehicle and System Modelling

In this chapter...

2.1   2D System

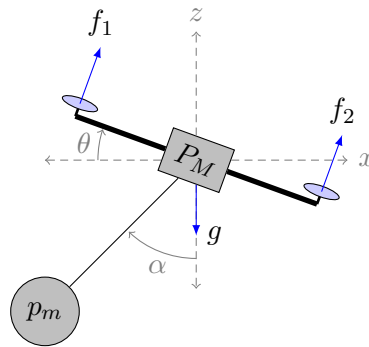Figure 2.1 shows a image. The graph shows the angle between mass ang gravity vector (α).

Figure 2.1: Two-dimensional Model of a Quadrotor with a Suspended Payload

Bibliography

[1] M. M. Nicotra, E. Garone, R. Naldi, and L. Marconi, "Nested saturation control of an UAV carrying a suspended load," *Proceedings of the American Control Conference*, pp. 3585–3590, 2014.

Appendix A

Project Planning Schedule

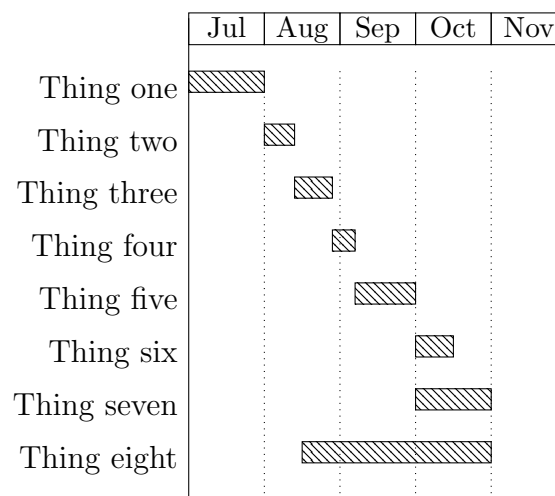|	Jul	Aug	Sep	Oct	Nov
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Thing two		▨			
Thing three		▨			
Thing four			▨		
Thing five			▨		
Thing six				▨	
Thing seven				▨	
Thing eight		▨▨▨			

Figure A.1: Project Time Line

Appendix B

Outcomes Compliance

Appendix C

Parameters Used

This appendix serves as a reference to the parameters used for the simulated quadrotor and load system.

Table C.1: Specifications of Quadrotor Payload System

Parameter	Value
M	1 kg
m	0.5 kg
L	0.5 m
Max θ	45 degrees
Max total thrust	40 N
ρ	$1.225 kg/m^3$
C_D	1
b_α	0.0001
S_z	$0.2m^2$
S_x	$0.2m^2$