The quad copter is controlled using an android app which uses communicates with a Bluetooth module which sends serial data to an Arduino. Bluetooth was chosen as a communication protocol as it provides simple interface using a mobile app, which is also very customizable, and allows for multiple methods for sending data, and allows for displaying received data in recognizable ways. The buad rate of the Bluetooth communication is 9600, and this is preset in the app. The Arduino receives control information in the form of serial data in the form of packets (ex. @LX120Y130!), which are decoded and processed then sent to another Arduino which deals with the stabilization of the quad over I2C. I2C was chosen for the communication between the two Arduinos as it only requires 2 connections, and because the master Arduino (the one used for control) requests the data to be sent from the slave Arduino, which means communication only takes place when necessary. Another motive to use I2C is that the master Arduino communicates with the accelerometer/gyroscope using I2C.