



# Design, Implementation and Evaluation of an Incremental Nonlinear Dynamic Inversion Controller for a Nano-Quadrotor

—

Entwurf, Implementierung und Evaluierung eines Inkrementellen Nichtlinearen Dynamischen  
Inversionsreglers für einen Nano-Quadrotor

## Semesterarbeit

Author: Evghenii Volodscoi

Matriculation number: 03663176

Supervisor: Dr. Ewoud Smeur

April 2020



## **Statutory Declaration**

I, Evghenii Volodscoi, declare on oath towards the Institute of Flight System Dynamics of Technische Universität München, that I have prepared the present Semester Thesis independently and with the aid of nothing but the resources listed in the bibliography.

This thesis has neither as-is nor similarly been submitted to any other university.

Garching,



## **Kurzfassung**

*Deutsche Kurzfassung der Arbeit.*

## **Abstract**

*English abstract of the thesis.*



## Table of Contents

1	Introduction	1
1.1	Motivation . . . . .	1
1.2	Contribution of the Thesis . . . . .	1
1.3	Structure of the Thesis . . . . .	1
2	Theoretical Background	2
2.1	Nonlinear Dynamic Inversion . . . . .	2
2.2	Incremental Nonlinear Dynamic Inversion . . . . .	2
3	Implementation	3
3.1	Research Quadrotor . . . . .	3
3.2	Simulink Model . . . . .	3
3.2.1	Purpose . . . . .	3
3.2.2	Structure . . . . .	3
3.2.3	Simulation Results . . . . .	3
3.3	Implementation on Hardware . . . . .	3
3.3.1	Testing with contact Forces and Moments . . . . .	3
4	Results	4
5	Discussion	5
	Appendix	i





## List of Figures



## List of Tables



## Table of Acronyms

Acronym	Description
ADF	Automatic Direction Finder
ADI	Automatic Direction Indicator



## Table of Symbols

### Latin Letters

Symbol	Unit	Description
$F$	$N$	Force
$g$	$m/s^2$	Gravitational acceleration

### Greek Letters

Symbol	Unit	Description
$\alpha$	$rad$	Angle of attack
$\zeta$	–	Damping of a linear second order system

### Indices

Symbol	Unit	Description
$m$		Variable related to pitch moment
$W$		Wind





# **1 Introduction**

## **1.1 Motivation**

## **1.2 Contribution of the Thesis**

## **1.3 Structure of the Thesis**

## **2 Theoretical Background**

### **2.1 Nonlinear Dynamic Inversion**

### **2.2 Incremental Nonlinear Dynamic Inversion**

## **3 Implementation**

### **3.1 Research Quadrotor**

### **3.2 Simulink Model**

#### **3.2.1 Purpose**

#### **3.2.2 Structure**

#### **3.2.3 Simulation Results**

### **3.3 Implementation on Hardware**

#### **3.3.1 Testing with contact Forces and Moments**

## 4 Results

## 5 Discussion

## Appendix