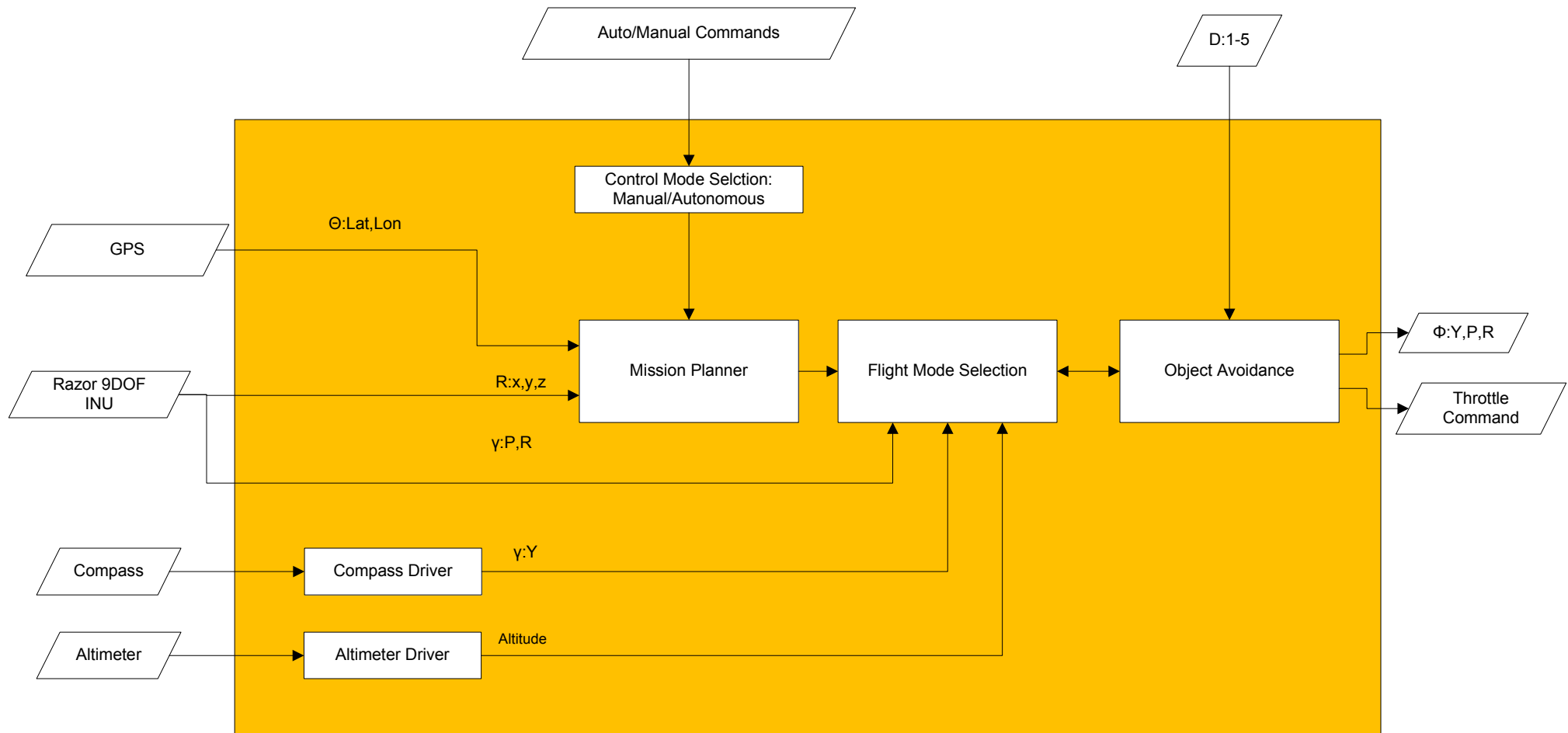
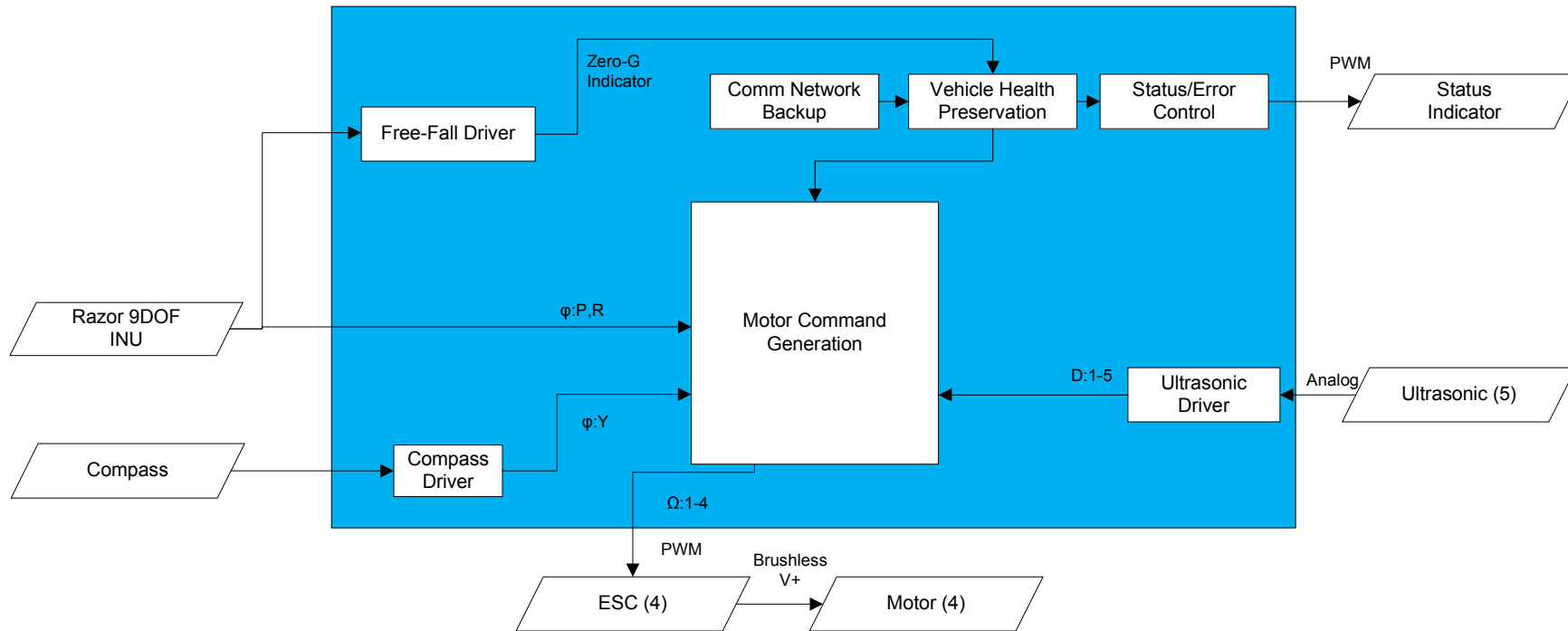


# UPDATE!!!

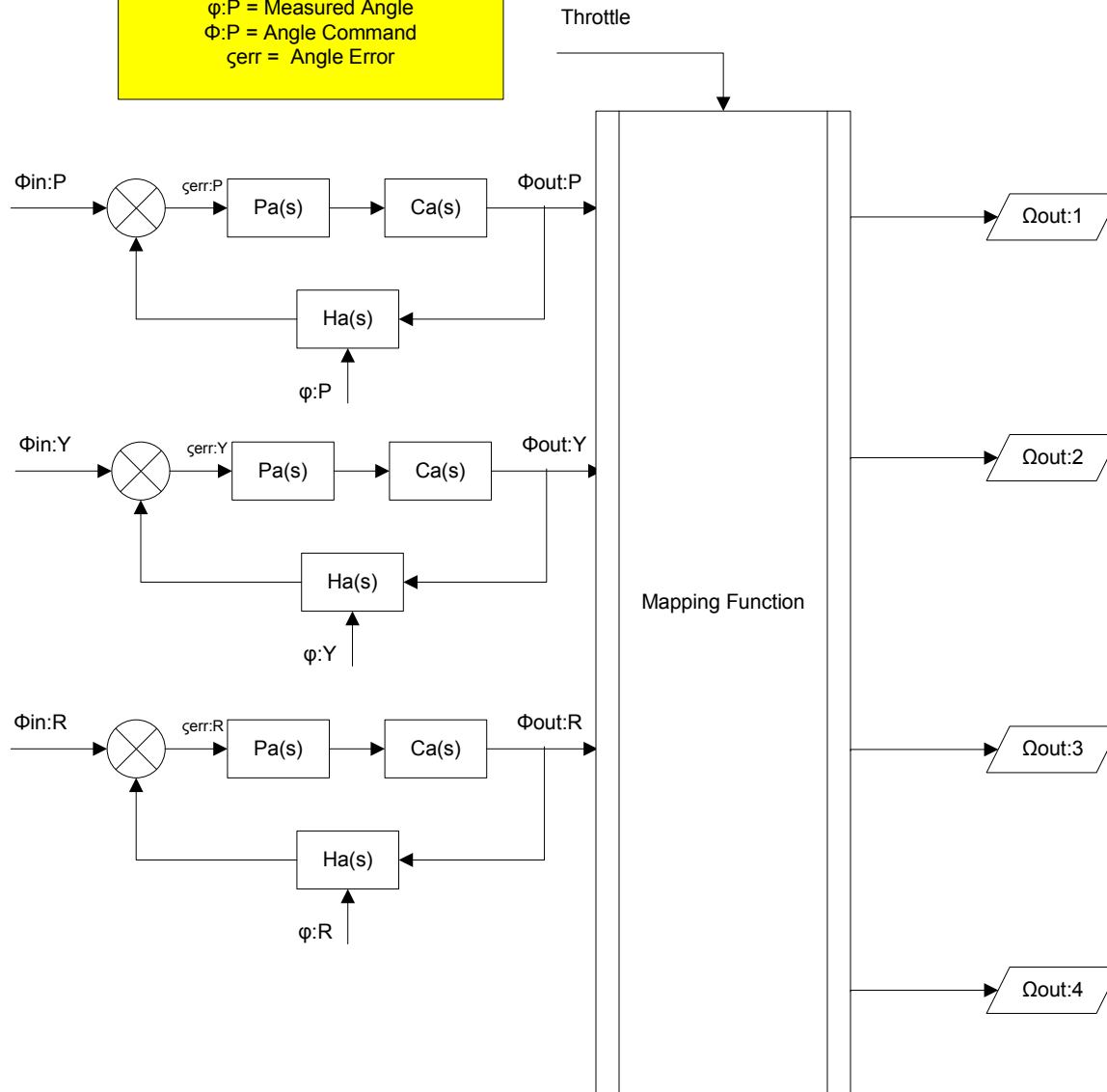


## Secondary Controller



# UPDATE!!!

$Ca(s) = K_Pp + K_Pi*s + k_{Pd}/s$   
 $Ha(s)$  = Sensor Gain  
 $Pa(s)$  = Plant Transfer Function  
 For  $j$  = Pitch,Yaw,Roll  
 $\phi:P$  = Measured Angle  
 $\Phi:P$  = Angle Command  
 $\zeta err$  = Angle Error



Mapping Function:  
 Constants: MID\_RANGE  
 $\Omega_{in}:1 = \Phi_{out}:P, \Phi_{out}:Y, \Phi_{out}:R, Throttle$