



Uncrewed Aerial Vehicle Flight Control Module Specifications Document

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Contents

1 SCOPE	6
2 APPLICABLE DOCUMENTS	7
3 STAKEHOLDER REQUIREMENTS	8
3.1 Physical	8
3.2 Behavioral	8
3.3 Functional	8
3.4 Environmental	8
3.5 Ethical	9
4 ENGINEERING REQUIREMENTS	10
4.1 System Requirements	11
4.1.1 Interfaces	11
4.1.2 Processing	12
4.1.3 Built in HW Capabilities	13
4.1.4 HW Interfaces	13
4.1.5 HAL	13
4.1.6 Power Management	14
4.1.7 Sub-Parts	14
4.2 Planner	15
4.2.1 Interfaces	15
4.2.2 General Requirements	15
4.2.3 Waypoint Planner	16
4.2.4 RC Mixer	16
4.2.5 State Select	17
4.3 Controller	18
4.3.1 Interfaces	18
4.3.2 Preprocessor	18
4.3.3 PVA Controller	19
4.3.4 ATL Controller	20
4.3.5 Control Distributor	21
4.4 Navigation	22
4.4.1 Interfaces	22
4.4.2 Sensor Selector	22
4.4.3 Estimator	23

4.5	Logger	25
4.5.1	Interfaces	25
4.5.2	General Requirements	26
4.5.3	Storage	26
4.5.4	Transmitt	26
5	VERIFICATION OF REQUIREMENTS	27
5.1	System Verification	28
5.1.1	Processing	28
5.1.2	Built in HW Capabilities	28
5.1.3	HW Interfaces	28
5.1.4	HAL	28
5.1.5	Power Management	28
5.2	Planner Verification	29
5.2.1	Waypoint Planner	29
5.2.2	RC Mixer	29
5.2.3	State Select	29
5.3	Controller Verification	30
5.3.1	Preprocessor	30
5.3.2	PVA Controller	30
5.3.3	ATL Controller	31
5.3.4	Control Distributor	32
5.4	Navigation Verification	34
5.4.1	Sensor Selector	34
5.4.2	Estimator	35
5.5	Logger Verification	37
5.5.1	Storage	37
5.5.2	Transmitt	37
5.6	Verification Methods	38
5.7	Verify Coverage of Stakeholder Requirements	39

Specifications

1 SCOPE

- (a) **General:** This document defines the design and verification requirements for the Uncrewed Aerial Vehicle (UAV) Flight Control Module (FCM). The system provides the core functionality required for stable, autonomous, and remote operation of a fixed-wing aircraft. It manages flight stabilization, navigation, control, and mission execution through integrated sensing, actuation, and computation. The FCM shall support interfacing with an external companion system for higher-level mission planning and enable autonomous operation in communication-limited environments, including navigation to a designated area and precision landing.
- (b) **Acronyms:**
- (i) UAV: Uncrewed Aerial Vehicle
 - (ii) FCM: Flight Control Module
 - (iii) HAL: Hardware Abstraction Layer
 - (iv) GPS: Global Positioning System
 - (v) IMU: Inertial Measurement Unit
 - (vi) PVA: Position/Velocity/Acceleration
 - (vii) ATL: Attitude/Throttle-Level
 - (viii) SD: Secure Digital

2 APPLICABLE DOCUMENTS

The following documents shown shall form part of the specifications for this project. In the event of a conflict between requirements, priority shall first go to the contract, second to this document, and lastly to these reference documents.

- (a) **Government Documents** *This is where to put MIL-Specs, MIL-STDs, NASA specs and so forth. Be sure to include the revision level and date.*
- (b) **Industry Documents** *This is where to put ANSI, ASTM, ASME, IEEE, Company specifications and so forth. Both this section and government documents can be divided up into logical subcategories.*

3 STAKEHOLDER REQUIREMENTS

3.1 Physical

- 3.1.1 The device must fit inside of a typical RC airplane.
- 3.1.2 The flight controller must be battery powered.
- 3.1.3 The device must have ports commonly used for connecting parts used in flight.

3.2 Behavioral

- 3.2.1 The flight controller must keep stable drone flight during operation.
- 3.2.2 The flight controller must handle autonomous flight as well as teleoperated flight.
- 3.2.3 Regardless of control method, the flight controller must avoid the plane losing stability or crashing.
- 3.2.4 The flight controller must be able to be configured with the parameters of a given plane.

3.3 Functional

- 3.3.1 The flight controller must provide proper inputs to the control surfaces of the drone.
- 3.3.2 The flight controller must accept a programmed mission plan for autonomous flight.
- 3.3.3 The flight controller must read from on board sensors in order to provide stable controls to the plane.
- 3.3.4 The flight controller must allow for additional sensors to be connected.

3.4 Environmental

- 3.4.1 The flight controller must be able to operate during potentially rough flight of a small airplane.
- 3.4.2 The flight controller must work the same even when the temperature or air pressure changes.
- 3.4.3 The flight controller must be able to function regardless of vibrations from the plane.

3.5 Ethical

- 3.5.1 The flight controller must have safety checks to ensure sufficient power at least 5 minutes of flight.
- 3.5.2 In the event of a failure the flight controller must attempt to land safely instead of simply crashing.
- 3.5.3 The system must report and log failures of flight components.

4 ENGINEERING REQUIREMENTS

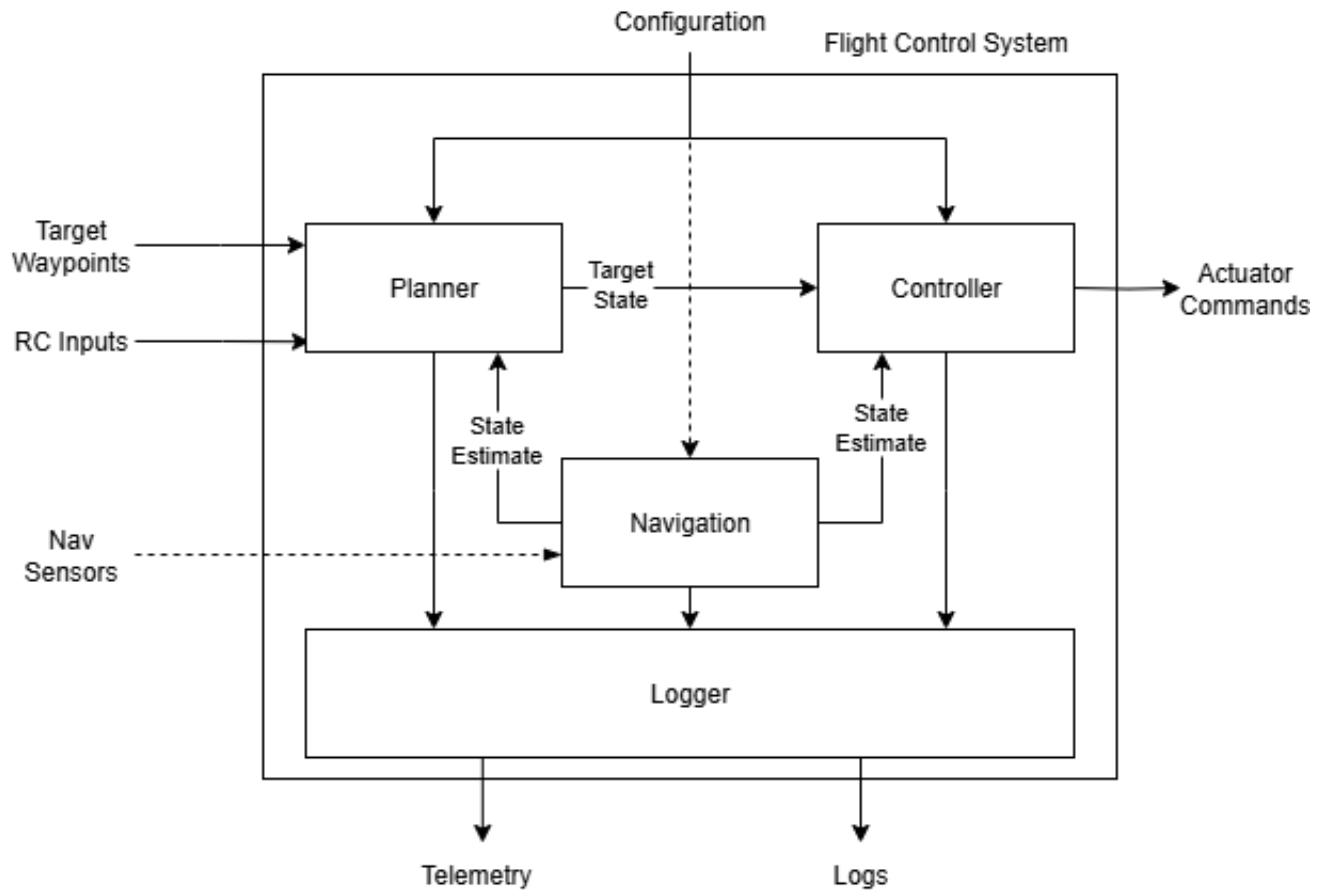


Figure 1. System functional diagram

4.1 System Requirements

The System provides the hardware and software foundation for all onboard modules. It includes processing, hardware capabilities, interfaces, hardware abstraction, and power management.

The System is comprised of five main parts: Processing, Built in HW Capabilities, HW Interfaces, HAL, and Power Management.

4.1.1 Interfaces

4.1.1.1 Inputs

- 4.1.1.1.1 All submodules require configuration parameters that dictate their operation. These parameters will all be contained in a YAML file required for operation start. These configuration parameters will be different dependant on the individual submodule, and that submodule will define the contents of its own configuration. In software, the parameters will be passed as a predefined object, referred to as a struct, though there is no requirement to utilize the C programming language and it's associated structs.
- 4.1.1.1.2 Waypoints are defined as a time index series of LLA points. Waypoints do not require an orientation or velocity component to avoid overconstraining the Planner submodule.
- 4.1.1.1.3 RC inputs are defined as the literal signals received from the RC receiver. This includes the raw stick inputs, as well as any auxiliary channels. The layout of these channels will be defined in the configuration parameters for a specific transmitter.
- 4.1.1.1.4 External sensor data is defined as raw data received from any sensors not directly connected to the onboard PCB. This includes sensors connected via serial communication.

4.1.1.2 Outputs

- 4.1.1.2.1 Peripheral commands are defined as commands to control onboard motors and servos. These commands are generated by the Controller submodule.

4.1.1.3 Internal

- 4.1.1.3.1 UAV state estimates are defined as the best estimate of the UAV's current position, orientation, velocity, and angular velocity. This estimate is generated by the Navigation submodule.
- 4.1.1.3.2 Desired states are defined as a time index series of the positions, orientations, velocities, and angular velocities. These desired states are generated by the Planner submodule.

- 4.1.1.3.3 State mask is defined as a bitmask indicating which states are to be controlled by the Controller submodule, and is generated by the Planner submodule.
- 4.1.1.3.4 RC adjustments are defined as trims and scaling factors for each control input. Based on the transmitter mapping, the adjustments will be applied to the raw RC inputs and passed to the Logger for logging. These adjustments are generated by the Planner submodule.
- 4.1.1.3.5 Raw control outputs are defined as the initial values calculated by the Controller for percent thrust, aileron deflection, elevator deflection, and rudder deflection. These values aren't directly used, but are passed to the Logger for logging purposes.
- 4.1.1.3.6 Error reports are defined as any fault or error detected by the HAL or Planner, Navigation, or Controller submodules during operation. These reports are passed to the Logger for logging and potential transmission. Error reports shall include a timestamp, error code, and description of the error.
- 4.1.1.3.7 Onboard sensor data is defined as raw data received from any sensors directly connected to the onboard PCB.

4.1.2 Processing

The Processing part provides the computational resources and pipeline for all onboard software modules.

- 4.1.2.1 The flight module shall provide a central processor to execute software instructions.
- 4.1.2.2 The central processor of the flight module shall support a processing speed such that the hyperperiod of all of the tasks is 2.5 ms(400 Hz).
- 4.1.2.3 The central processor of the flight module shall employ a real-time operating system to handle task scheduling.
- 4.1.2.4 The central processor of the flight module shall support task isolation, such that a failure of one task does not cause failure of another task.
- 4.1.2.5 The central processor of the flight module shall monitor system diagnostics in order to catch faults.
- 4.1.2.6 The central processor of the flight module shall provide recovery for detected faults.

4.1.3 Built in HW Capabilities

Built-in hardware capabilities include sensors, and onboard peripherals required for mission execution.

4.1.3.1 The flight module shall provide an on-board IMU.

4.1.3.2 The flight module shall provide an on-board RC receiver for teleoperation.

4.1.3.3 The flight module shall provide an on-board micro-SD card reader for data storage.

4.1.3.4 The flight module shall provide power monitoring and regulation.

4.1.4 HW Interfaces

Hardware interfaces provide connectivity between onboard modules and external devices.

4.1.4.1 Support standard communication protocols.

4.1.4.2 Ensure robust electrical and logical connections.

4.1.4.3 Provide diagnostics for interface health.

4.1.5 HAL

The Hardware Abstraction Layer (HAL) provides a uniform interface to hardware resources, abstracting device specifics from higher-level modules. All configuration of the system will be done through the HAL. All necessary configuration information will be included in the YAML file which will be read in at program initialization.

4.1.5.1 Requirements

4.1.5.1.1 The HAL shall provide a scope and deliverables document detailing the capabilities and resources offered.

4.1.5.1.2 The HAL scope and deliverables document shall include support to at least the following functionalities:

- GPIO pin control
- I2C/SPI bus management
- UART serial communication
- USB 2.0 serial communication
- CAN communication

- Micro SD card read and write support
- ADC support
- Timer control
- Interrupt control
- Generic device interfacing (Requires associated driver)

4.1.5.1.3 The HAL shall provide an ICD outlining the APIs utilized for all functionality described in the scope and deliverables document.

4.1.5.1.4 The HAL ICD shall describe the ownership of all memory for all functions receiving or returning memory pointers.

4.1.5.1.5 The HAL shall provide common status codes which are returned from all HAL functions to avoid silent failures.

4.1.5.1.6 The HAL shall provide a method of gracefully handling faults and reporting those faults.

4.1.5.1.7 The HAL shall adhere to all coding standards described in §X.X.X

4.1.6 Power Management

Power Management ensures efficient and reliable power distribution to all system components.

4.1.6.1 Monitor and regulate power supply.

4.1.6.2 Support low-power and standby modes.

4.1.6.3 Protect against overcurrent and undervoltage.

4.1.7 Sub-Parts

The System is comprised of four functional sub-parts:

4.1.7.1 Planner

4.1.7.2 Controller

4.1.7.3 Navigation

4.1.7.4 Logger

4.2 Planner

The purpose of the Planner is to generate a series of realizable states for the UAV. The planner allows for both autonomous and pilot-directed operation. Inputs from both autonomous and pilot-directed modes are evaluated and potentially adjusted to fit safety and feasibility constraints. The inputs are evaluated based on the current UAV state and the current tolerances from configuration parameters. The Planner is comprised of three submodules: Waypoint Planner, RC Mixer, and State Select. Each has aids in the overall functionality of the Planner.

4.2.1 Interfaces

4.2.1.1 Inputs

4.2.1.1.1 The planner requires the mission parameters and UAS tolerances when generating waypoints. These tolerances shall include maximum and minimum airspeeds, maximum g-load, maximum climb and descent rates, maximum altitude, maximum bank angle, and minimum turn radius. Additionally, the planner's configuration parameters shall include an operating mode to determine whether RC inputs or generated waypoints are used to generate the desired states.

4.2.1.1.2 Waypoints as defined in 4.1.1.1.X.

4.2.1.1.3 RC inputs as defined in 4.1.1.1.Y.

4.2.1.1.4 UAV state estimates as defined in 4.1.1.3.Z.

4.2.1.2 Outputs

4.2.1.2.1 Desired States as defined in 4.1.1.3.X.

4.2.1.2.2 State mask as defined in 4.1.1.3.Y.

4.2.1.2.3 Logging data as defined in 4.1.1.3.Z.

4.2.1.3 Internal

4.2.1.3.1 Planned waypoint states. These inputs are generated by the Waypoint Planner submodule and consumed by the State Select submodule where they'll be multiplexed based on operating mode.

4.2.2 General Requirements

4.2.2.1 The Planner shall accept the inputs defined in §4.2.1.1 and produce a time-ordered sequence of desired states at no slower than 500 Hz.

4.2.2.2 For all output states:

$$\begin{aligned}V_{\min} \leq v \leq V_{\max}, & \text{ (airspeed)} \\|\phi| \leq \phi_{\max}, & \text{ (bank angle)} \\|\dot{h}| \leq \dot{h}_{\max}, & \text{ (vertical speed)} \\\kappa \leq 1/R_{\min}, & \text{ (turn rate)} \\n \leq n_{\max}, & \text{ (load factor)}\end{aligned}$$

Where V_{\min} , V_{\max} , ϕ_{\max} , \dot{h}_{\max} , R_{\min} , and n_{\max} are the UAV tolerances input to the Planner defined in §4.2.1.1.1.

4.2.2.3 The Planner shall validate input presence, ranges, units, and timestamps. Invalid inputs shall result in rejection of the current input and preservation of last valid output for ≤ 1 cycle.

4.2.2.4 The Planner shall log all input and output data during operation. Additionally, all detected errors will be logged with reason and timestamp.

4.2.2.5 The Planner shall adhere to all coding standards defined in §X.X.X.

4.2.3 Waypoint Planner

The Waypoint Planner submodule is responsible for generating feasible waypoint trajectories during autonomous flight. It consumes high level waypoints, and creates a series of states that are determined to be safe and feasible based on the current UAV state and configuration parameters.

4.2.3.1 The Waypoint Planner shall include each commanded waypoint as a goal in the output sequence when inclusion does not violate any constraint in §4.2.2.2, otherwise, it shall mark the waypoint as unreachable and produce the state that best approximates the commanded waypoint while still satisfying all constraints.

4.2.4 RC Mixer

The RC Mixer submodule is responsible for generating desired states based on pilot RC inputs. These inputs will be adjusted to the level defined in the configuration parameters to aid in preserving the safety of the UAV. The adjusted inputs will then be converted to desired states for the UAV to achieve.

4.2.4.1 The RC Mixer shall always produce a valid output regardless of input validity.

4.2.4.2 The RC Mixer shall converge to zero climb rate and zero turn rate in the absence of valid RC inputs within 2 seconds.

4.2.4.3 The RC Mixer shall log all RC inputs and generated outputs with timestamps, any errors detected, and any adjustments made to the inputs to preserve safety.

4.2.5 State Select

The State Select submodule is responsible for multiplexing between the Waypoint Planner and RC Mixer outputs based on the current operating mode. Additionally, the State Select submodule is responsible for determining the state mask passed to the Controller based on the current operating mode.

4.2.5.1 The State Select shall always produce a valid output regardless of input validity.

4.3 Controller

The Controller computes actuator setpoints from planned trajectories and state estimates. It implements required control algorithms and scheduling, ensuring safe and efficient operation of the UAV actuators. The Controller is comprised of four submodules: Preprocessor, PVA Controller, ATL Controller, and Control Distributor. Each submodule contributes to translating planned trajectories into actuator commands.

4.3.1 Interfaces

4.3.1.1 Inputs

4.3.1.1.1 Planned setpoints defined in 4.1.1.3.X.

4.3.1.1.2 State mask as defined in 4.1.1.3.Y.

4.3.1.1.3 State estimates defined in 4.4.1.2.1.

4.3.1.1.4 Controller configuration parameters.

4.3.1.2 Outputs

4.3.1.2.1 Actuator setpoints for ailerons, elevator, rudder, and throttle(s).

4.3.1.2.2 Logging data for control events and diagnostics.

4.3.1.3 Internal

4.3.1.3.1 Position, velocity, and acceleration state and setpoints.

4.3.1.3.2 Attitude, angular rate, and throttle state and setpoints.

4.3.1.3.3 Attitude, angular rate, and throttle targets.

4.3.1.3.4 Intermediary setpoints for ailerons, elevator, rudder, and throttle(s).

4.3.2 Preprocessor

The Preprocessor submodule is responsible for setting up inputs and setpoints for the controller chain given the desired operating mode.

4.3.2.1 The preprocessor shall consume planned setpoints as defined in 4.3.1.1.1.

4.3.2.2 The preprocessor shall consume state estimates as defined in 4.3.1.1.3.

4.3.2.3 The preprocessor shall output processed state and setpoints for the PVA controller as defined in 4.3.1.3.1.

- 4.3.2.4 The preprocessor shall output processed attitude and throttle state and setpoints for the ATL controller as defined in 4.3.1.3.2.
- 4.3.2.5 The preprocessor shall consume controller configuration parameters as defined in 4.3.1.1.4.
- 4.3.2.6 The preprocessor shall not consume more than 5% of the selected processing unit's bandwidth.
- 4.3.2.7 The preprocessor shall be functional agnostic to the UAV environment.
- 4.3.2.8 The preprocessor shall apply saturation and rate limits to setpoints determined by the controller configuration and UAV state.
- 4.3.2.9 The preprocessor shall log invalid or out-of-bounds inputs for diagnostics.
- 4.3.2.10 The preprocessor shall ensure safe defaults for missing or invalid inputs.
- 4.3.2.11 The preprocessor shall ensure safe operation under non-flight conditions.
- 4.3.2.12 The preprocessor shall enable and disable states and setpoints based on the current operating mode.
- 4.3.2.13 The preprocessor shall output the exact state it receives unless zeroing for disabled setpoints.
- 4.3.2.14 The preprocessor shall output the exact setpoints it receives modified only by slewing unless zeroing for disabled setpoints.

4.3.3 PVA Controller

The PVA (Position/Velocity/Acceleration) Controller submodule computes control setpoints to track planned trajectories and maintain the UAV along the desired path.

- 4.3.3.1 The PVA controller shall consume setpoints and state estimates as defined in 4.3.1.3.1.
- 4.3.3.2 The PVA controller shall output desired attitude and torque targets as defined in 4.3.1.3.3.
- 4.3.3.3 The PVA controller shall consume controller configuration parameters as defined in 4.3.1.1.4.
- 4.3.3.4 The PVA controller shall not consume more than 10% of the selected processing unit's bandwidth.

- 4.3.3.5 The PVA controller shall maintain stability with up to 20% sensor noise.
- 4.3.3.6 The PVA controller shall expose gains and tuning parameters via configuration.
- 4.3.3.7 The PVA controller shall reject external disturbances, such that tuning the gains allows for tracking a parabolic position input with maximum steady state error 2x the platform size.
- 4.3.3.8 The PVA controller shall ensure bounded errors and proper saturation handling.
- 4.3.3.9 The PVA controller shall log control errors and saturation events for diagnostics.
- 4.3.3.10 The PVA controller shall be stall aware and prevent commands that would lead to stalling.
- 4.3.3.11 The PVA controller shall expose setpoints for position, velocity, and acceleration in three dimensions.

4.3.4 ATL Controller

The ATL (Attitude/throttle-Level) Controller submodule translates higher-level commands into low-level actuator commands, respecting actuator limits and constraints.

- 4.3.4.1 The ATL controller shall consume setpoints and state estimates as defined in 4.3.1.3.2.
- 4.3.4.2 The ATL controller shall consume setpoints as defined in 4.3.1.3.3.
- 4.3.4.3 The ATL controller shall output low-level intermediary actuator commands as defined in 4.3.1.3.4.
- 4.3.4.4 The PVA controller shall consume controller configuration parameters as defined in 4.3.1.1.4.
- 4.3.4.5 The ATL controller shall not consume more than 10% of the selected processing unit's bandwidth.
- 4.3.4.6 The ATL controller shall maintain stability with up to 20% sensor noise.
- 4.3.4.7 The ATL controller shall expose gains and tuning parameters via configuration.
- 4.3.4.8 The ATL controller shall reject external disturbances, such that tuning the gains allows for tracking a ramp attitude input with maximum steady state error of 1 degree.
- 4.3.4.9 The ATL controller shall ensure bounded errors and proper saturation handling.

- 4.3.4.10 The ATL controller shall log control errors and saturation events for diagnostics.
- 4.3.4.11 The ATL controller shall be stall aware and prevent commands that would lead to stalling.
- 4.3.4.12 The ATL controller shall expose setpoints for attitude and angular velocity in three dimensions.
- 4.3.4.13 The ATL controller shall expose throttle setpoints independent of attitude and angular velocity.

4.3.5 Control Distributor

The Control Distributor submodule routes control outputs to the correct actuator channels, mapping and distributing logical control channels to physical hardware outputs.

- 4.3.5.1 The control distributor shall consume low-level intermediary actuator commands as defined in 4.3.1.3.4.
- 4.3.5.2 The control distributor shall output hardware actuator signals as defined in 4.3.1.2.1.
- 4.3.5.3 The control distributor shall consume controller configuration parameters as defined in 4.3.1.1.4.
- 4.3.5.4 The control distributor shall not consume more than 5% of the selected processing unit's bandwidth.
- 4.3.5.5 The control distributor shall be functional agnostic to the UAV environment.
- 4.3.5.6 The control distributor shall detect and handle hardware failures gracefully.
- 4.3.5.7 The control distributor shall support testing the configured output map while not in flight.
- 4.3.5.8 The control distributor shall be robust to configuration errors.
- 4.3.5.9 The control distributor shall log routing errors and hardware failures for diagnostics.
- 4.3.5.10 The control distributor shall attempt to continue operation in the presence of hardware output failures.
- 4.3.5.11 The control distributor shall disable outputs to all throttle channels when not in an armed flight mode.
- 4.3.5.12 The control distributor shall map logical control channels to physical hardware outputs based on configuration using the HAL defined in 4.1.5.

4.4 Navigation

The Navigation module provides accurate state estimation and sensor selection to support planning and control by running estimators, selecting appropriate sensors, and publishing state estimates. The Navigation module is comprised of two submodules: Sensor Selector and Estimator. Each submodule contributes to robust and accurate state estimation from available sensor inputs.

4.4.1 Interfaces

4.4.1.1 Inputs

4.4.1.1.1 IMU, GPS, barometer, and magnetometer data from all available units

4.4.1.1.2 Navigation configuration parameters

4.4.1.2 Outputs

4.4.1.2.1 Global position, velocity, attitude, and angular velocity state estimate and uncertainty with timestamp

4.4.1.2.2 Logging data for sensor selection and estimation events.

4.4.1.3 Internal

4.4.1.3.1 Selected IMU, GPS, barometer, and magnetometer sensor feeds

4.4.2 Sensor Selector

The Sensor Selector submodule evaluates available sensor inputs and using configuration selects the best sensors for the current conditions, ensuring robust operation and allowing user input.

4.4.2.1 The sensor selector unit shall consume all available sensor feeds defined in 4.4.1.1.1

4.4.2.2 The sensor selector unit shall consume sensor selection configuration as defined in 4.4.1.1.2

4.4.2.3 The sensor selector unit shall output selected sensor feeds for the estimator as defined in 4.4.1.3.1

4.4.2.4 The sensor selector shall not consume more than 5% of the selected processing unit's bandwidth.

4.4.2.5 The sensor selector shall be functional agnostic to the UAV environment.

- 4.4.2.6 The sensor selector shall expose safe fallbacks sensors if available when preferred sensors are unavailable.
- 4.4.2.7 The sensor selector shall use health indicators to avoid selecting faulty sensors.
- 4.4.2.8 The sensor selector shall log sensor selection decisions for diagnostics.
- 4.4.2.9 The sensor selector shall expose priority and fallback choices for sensors based on configuration.
- 4.4.2.10 The sensor selector shall only execute upon reception of new sensor data.

4.4.3 Estimator

The Estimator submodule fuses selected sensor inputs using sensor fusion algorithms to produce the best estimate of the system state.

- 4.4.3.1 The estimator shall provide state estimate outputs and uncertainties as defined in 4.4.1.2.1.
- 4.4.3.2 The estimator shall consume selected sensor streams defined in 4.4.1.3.1.
- 4.4.3.3 The estimator shall comsume navigation configuration parameters as defined in 4.4.1.1.2.
- 4.4.3.4 The estimator shall log raw sensor inputs and state estimates for diagnostics.
- 4.4.3.5 The estimator shall not consume more than 10% of the selected processing unit's bandwidth.
- 4.4.3.6 The estimator shall estimate and compensate for signals with up to 20% noise.
- 4.4.3.7 The estimator shall estimate and correct biases in sensor measurements within 20%.
- 4.4.3.8 The estimator shall expose uncertainties that are accurate to 3 standad deviations.
- 4.4.3.9 The estimator shall use the configuration to be cognisant to sensor mounting orientations.
- 4.4.3.10 The estimator shall log inconsistant inputs and anomalies.
- 4.4.3.11 The estimator shall use timestamps to identify and drop stale data.
- 4.4.3.12 The estimator shall ensure proper timestamps accompany each output estimate.

4.4.3.13 The estimator shall provide a common interface for inputs of various measurement types.

4.4.3.14 The estimator shall expose interfaces with data that adheres to at most one body frame coordinate system and one inertial frame coordinate system.

4.5 Logger

The Logger records mission data and provides mechanisms for transmission or storage by collecting telemetry, writing to storage, and/or sending data via communications links. The Logger is comprised of two submodules: Storage and Transmitt. Each submodule handles data persistence and transmission for mission telemetry and diagnostic information.

4.5.1 Interfaces

4.5.1.1 Inputs

- 4.5.1.1.1 The Logger requires configuration parameters to determine where data is logged and sent, transmission rates, and data routing policies. These parameters will include file storage locations and transmission rates and protocols.
- 4.5.1.1.2 The Logger receives input waypoints from the Companion Computer as defined in 4.1.1.1.2.
- 4.5.1.1.3 The Logger receives desired states from the Planner as defined in 4.1.1.3.2.
- 4.5.1.1.4 The Logger receives the state mask from the Planner as defined in 4.1.1.3.3.
- 4.5.1.1.5 The Logger receives RC inputs from the Pilot as defined in 4.1.1.1.3.
- 4.5.1.1.6 The Logger receives adjustments to RC inputs from the Planner. These adjustments include trims and scaling factors of each control input.
- 4.5.1.1.7 The Logger receives raw sensor data from any onboard sensors as defined in 4.1.1.3.7 or external sensors as defined in 4.1.1.1.4.
- 4.5.1.1.8 The Logger receives state estimates from the Navigation as defined in 4.1.1.3.1.
- 4.5.1.1.9 The Logger receives raw control outputs from the Controller as defined in 4.1.1.3.5.
- 4.5.1.1.10 The Logger receives peripheral commands from the Controller as defined in 4.1.1.2.1.
- 4.5.1.1.11 The Logger receives any error reports from the Planner, Navigation, and Controller as defined in 4.1.1.3.6.

4.5.1.2 Outputs

- 4.5.1.2.1 The Logger outputs stored log files to the location defined in the configuration parameters.
- 4.5.1.2.2 The Logger outputs telemetry packets transmitted via communications link as defined in the configuration parameters.

4.5.2 General Requirements

4.5.2.1 The Logger shall support logging of all generated data from onboard modules.

4.5.2.2 The Logger shall support rate limiting for all logged data.

4.5.2.3 The Logger shall adhere to all coding standards defined in §X.X.X.

4.5.3 Storage

The Storage submodule is responsible for persisting telemetry and logs to onboard non-volatile memory, ensuring data is retained for later retrieval and analysis. The location and format of stored data can be defined via configuration parameters. However, if no configuration is provided, the Storage submodule will default to storing data in a predefined location in a standard format as defined in the proceeding requirements.

4.5.3.1 The Storage submodule shall have default storage location of '/logs/' on onboard non-volatile memory.

4.5.3.2 The Storage submodule shall default to storing data from each data stream in a '.log' file with timestamps for each entry.

4.5.3.3 The Storage submodule shall support configuration parameters to define custom storage locations and file formats for all logged data.

4.5.3.4 The Storage submodule shall support a sliding window of log files, based on either time duration or storage size limits defined in configuration parameters. The default shall be 4 hours and 10MB respectively.

4.5.3.5 The Storage submodule shall implement a verification mechanism such as checksums or hashes for all stored data.

4.5.4 Transmitt

The Transmitt submodule handles transmission of selected telemetry data to ground stations or other external systems via available communications links.

4.5.4.1 The Transmitt submodule shall support transmission to up to three external systems simultaneously.

4.5.4.2 The Transmitt submodule shall support both UDP and TCP transmission protocols.

5 VERIFICATION OF REQUIREMENTS

5.1 System Verification

5.1.1 Processing

- 5.1.1.1 Verify sufficient compute for all modules.
- 5.1.1.2 Verify support for real-time scheduling and isolation.
- 5.1.1.3 Verify fault tolerance and recovery.

5.1.2 Built in HW Capabilities

- 5.1.2.1 Verify provision of required sensors and actuators.
- 5.1.2.2 Verify hardware health monitoring.
- 5.1.2.3 Verify support for hardware expansion where feasible.

5.1.3 HW Interfaces

- 5.1.3.1 Verify support for standard communication protocols.
- 5.1.3.2 Verify robust electrical and logical connections.
- 5.1.3.3 Verify diagnostics for interface health.

5.1.4 HAL

- 5.1.4.1 Verify exposure of consistent APIs for hardware access.
- 5.1.4.2 Verify isolation of hardware changes from application logic.
- 5.1.4.3 Verify support for safe fallback on hardware faults.

5.1.5 Power Management

- 5.1.5.1 Verify monitoring and regulation of power supply.
- 5.1.5.2 Verify support for low-power and standby modes.
- 5.1.5.3 Verify protection against overcurrent and undervoltage.

5.2 Planner Verification

5.2.1 Waypoint Planner

- 5.2.1.1 Verify consumption of waypoints and configuration parameters.
- 5.2.1.2 Verify output of planned waypoints.
- 5.2.1.3 Verify execution within allocated CPU and power budgets.
- 5.2.1.4 Verify performance across expected environmental conditions.
- 5.2.1.5 Verify adherence to safety constraints.
- 5.2.1.6 Verify modular design and clear interfaces.
- 5.2.1.7 Verify compliance with applicable software development standards.

5.2.2 RC Mixer

- 5.2.2.1 Verify consumption of required items.
- 5.2.2.2 Verify output of required items.
- 5.2.2.3 Verify execution within allocated CPU and power budgets.
- 5.2.2.4 Verify performance across expected environmental conditions.
- 5.2.2.5 Verify adherence to safety constraints.
- 5.2.2.6 Verify modular design and clear interfaces.
- 5.2.2.7 Verify compliance with applicable software development standards.

5.2.3 State Select

- 5.2.3.1 Verify consumption of required items.
- 5.2.3.2 Verify output of required items.
- 5.2.3.3 Verify execution within allocated CPU and power budgets.
- 5.2.3.4 Verify performance across expected environmental conditions.
- 5.2.3.5 Verify adherence to safety constraints.
- 5.2.3.6 Verify modular design and clear interfaces.
- 5.2.3.7 Verify compliance with applicable software development standards.

5.3 Controller Verification

5.3.1 Preprocessor

- 5.3.1.1 The Preprocessor shall be verified by supplying planned setpoints and state estimates under all supported operating modes and confirming that processed outputs match expected values for each mode.
- 5.3.1.2 The Preprocessor shall be verified by introducing missing, invalid, or out-of-bounds inputs and confirming that safe defaults are substituted, last valid outputs are preserved for up to one cycle, and all such events are logged with reason and timestamp.
- 5.3.1.3 The Preprocessor shall be verified by changing controller configuration parameters and confirming that enabling/disabling of states and setpoints occurs as specified, and that zeroing or slewing is applied only to disabled setpoints.
- 5.3.1.4 The Preprocessor shall be verified by applying rapid mode transitions (i.e. idle to flight, flight to disarmed) and confirming that only expected states are zeroed or slewed, and that outputs remain stable.
- 5.3.1.5 The Preprocessor shall be verified by measuring execution time per control cycle on the target platform and confirming it remains below 5% of the total loop period.
- 5.3.1.6 The Preprocessor shall be verified by repeating functional tests under simulated environmental conditions (temperature, vibration, sensor delay) and confirming consistent results.
- 5.3.1.7 The Preprocessor shall be verified by injecting out-of-range setpoints and confirming that saturation and rate limiting are properly applied according to configuration and UAV state.
- 5.3.1.8 The Preprocessor shall be verified by simulating non-flight conditions and confirming that outputs are safe and no actuator commands are issued.
- 5.3.1.9 The Preprocessor shall be verified by reviewing diagnostic logs to confirm that all detected input faults and mode transitions are accurately recorded.

5.3.2 PVA Controller

- 5.3.2.1 The PVA Controller shall be verified by applying step, ramp, and parabolic position commands and confirming that output attitude and torque targets follow the desired trajectory with steady-state error less than twice the defined platform size.

- 5.3.2.2 The PVA Controller shall be verified by injecting known disturbances (i.e. wind bias, external acceleration) and verifying disturbance rejection through bounded tracking errors.
- 5.3.2.3 The PVA Controller shall be verified by sweeping gain parameters and confirming the effect on closed-loop stability and tracking performance.
- 5.3.2.4 The PVA Controller shall be verified by providing invalid or missing setpoints and confirming that bounded errors and safe fallback behavior are observed.
- 5.3.2.5 The PVA Controller shall be verified by measuring computation duration per cycle and confirming processing load remains within 10% of available control cycle time.
- 5.3.2.6 The PVA Controller shall be verified by introducing up to 20% sensor noise and confirming maintained stability and bounded output.
- 5.3.2.7 The PVA Controller shall be verified by running tests with different gain and tuning parameter configurations and confirming that changes are reflected in controller response.
- 5.3.2.8 The PVA Controller shall be verified by driving control inputs to cause near-saturation conditions and confirming proper limit enforcement and diagnostic logging.
- 5.3.2.9 The PVA Controller shall be verified by simulating stall-prone conditions and confirming that attitude commands are limited to avoid stall regions.
- 5.3.2.10 The PVA Controller shall be verified by reviewing logs to confirm that all control errors and saturation events are recorded with timestamps.
- 5.3.2.11 The PVA Controller shall be verified by confirming that position, velocity, and acceleration setpoints are generated in all three axes and correctly propagated to dependent modules.

5.3.3 ATL Controller

- 5.3.3.1 The ATL Controller shall be verified by applying known attitude and throttle setpoints and confirming that output actuator commands achieve the target within allowable error.
- 5.3.3.2 The ATL Controller shall be verified by performing ramp attitude input tests and verifying maximum steady-state tracking error does not exceed 1 degree.

- 5.3.3.3 The ATL Controller shall be verified by varying configuration parameters and confirming correct mapping of gain settings to response dynamics.
- 5.3.3.4 The ATL Controller shall be verified by providing invalid or missing setpoints and confirming that bounded errors and safe fallback behavior are observed.
- 5.3.3.5 The ATL Controller shall be verified by measuring computational latency per cycle and verifying utilization under 10% of total control loop time.
- 5.3.3.6 The ATL Controller shall be verified by applying synthetic sensor noise (up to 20%) and external disturbances to confirm maintained control stability.
- 5.3.3.7 The ATL Controller shall be verified by running tests with different gain and tuning parameter configurations and confirming that changes are reflected in controller response.
- 5.3.3.8 The ATL Controller shall be verified by forcing actuator saturation conditions and confirming bounded error behavior and saturation logging.
- 5.3.3.9 The ATL Controller shall be verified by simulating aerodynamic stall conditions and confirming throttle and attitude limits are enforced.
- 5.3.3.10 The ATL Controller shall be verified by reviewing logs to confirm that all control errors and saturation events are recorded with timestamps.
- 5.3.3.11 The ATL Controller shall be verified by confirming that attitude and angular velocity setpoints are generated in all three axes, and throttle setpoints are independent of attitude and angular velocity.

5.3.4 Control Distributor

- 5.3.4.1 The Control Distributor shall be verified by applying known intermediary actuator commands and verifying correct mapping to physical actuator outputs based on configuration.
- 5.3.4.2 The Control Distributor shall be verified by conducting signal continuity checks from logical control channels to each actuator interface pin.
- 5.3.4.3 The Control Distributor shall be verified by executing non-flight output mapping tests and confirming correct routing of signals to simulated actuator hardware.
- 5.3.4.4 The Control Distributor shall be verified by changing configuration parameters and confirming that logical-to-physical channel mapping updates as expected.

- 5.3.4.5 The Control Distributor shall be verified by measuring task timing and verifying utilization below 5% of total processing bandwidth.
- 5.3.4.6 The Control Distributor shall be verified by simulating actuator line failure or hardware disconnect and confirming that fallback or degraded mode operation occurs.
- 5.3.4.7 The Control Distributor shall be verified by running tests in various environmental conditions and confirming robust operation.
- 5.3.4.8 The Control Distributor shall be verified by confirming that throttle outputs are disabled when in disarmed mode.
- 5.3.4.9 The Control Distributor shall be verified by inducing configuration mismatches and verifying the system logs routing errors and maintains control on remaining channels.
- 5.3.4.10 The Control Distributor shall be verified by injecting single-output hardware faults and confirming operation continuity and logging of the event.
- 5.3.4.11 The Control Distributor shall be verified by cross-checking logical-to-physical channel mapping with configuration tables for correctness.

5.4 Navigation Verification

5.4.1 Sensor Selector

- 5.4.1.1 The Sensor Selector shall be verified by connecting multiple functioning IMUs, GPS units, barometers, and magnetometers to the system and observing that data from each is received and processed during operation.
- 5.4.1.2 The Sensor Selector shall be verified by loading different sensor configuration files and observing that the module updates its active sensor preferences and priorities according to each configuration.
- 5.4.1.3 The Sensor Selector shall be verified by running the system with several sensors of each type and confirming that the Estimator receives data only from the sensors selected by the Sensor Selector.
- 5.4.1.4 The Sensor Selector shall be verified by operating the system under representative load conditions and timing selection cycles to confirm that selection operations complete within 5% of total available processing time.
- 5.4.1.5 The Sensor Selector shall be verified by running flight-equivalent tests in varied conditions, such as static, moving, and magnetically disturbed environments, and confirming consistent sensor selection behavior and output availability.
- 5.4.1.6 The Sensor Selector shall be verified by disabling the highest-priority sensor during operation and confirming that the module automatically switches to a valid fallback sensor without interrupting output availability.
- 5.4.1.7 The Sensor Selector shall be verified by injecting simulated sensor faults (i.e. unrealistic values or loss of updates) and confirming that the module excludes those sensors from selection.
- 5.4.1.8 The Sensor Selector shall be verified by executing a sequence of sensor connection and disconnection events and confirming that each selection change and its rationale are recorded in the system log.
- 5.4.1.9 The Sensor Selector shall be verified by configuring sensors with distinct priority levels and observing that the selected sensors match the expected order of precedence and fallback defined in configuration.
- 5.4.1.10 The Sensor Selector shall be verified by providing new data at controlled intervals and confirming that selection processing only occurs immediately after new sensor data are received.

5.4.2 Estimator

- 5.4.2.1 The Estimator shall be verified by supplying known-position and -orientation sensor data and confirming that the estimated position, velocity, attitude, and angular rate outputs match ground truth within expected uncertainty bounds as defined in 4.4.1.2.1.
- 5.4.2.2 The Estimator shall be verified by providing the Estimator with only the selected sensor outputs from the Sensor Selector and confirming that no data from unselected sensors influence the results.
- 5.4.2.3 The Estimator shall be verified by loading different sets of navigation parameters and confirming that the estimator behavior and output statistics change according to those configurations.
- 5.4.2.4 The Estimator shall be verified by recording all sensor inputs and state outputs during a test run and confirming that both are available in the diagnostic log files for review.
- 5.4.2.5 The Estimator shall be verified by operating under representative mission conditions and measuring the total processing duration per update cycle to confirm that it remains within 10% of total available computational time.
- 5.4.2.6 The Estimator shall be verified by applying test sensor data containing up to 20% random noise and comparing estimated states against the known true trajectory to confirm that deviations remain within accuracy limits.
- 5.4.2.7 The Estimator shall be verified by adding a known constant bias to one or more sensor inputs and confirming that the estimator's bias correction reduces the resulting error to within 20% of the nominal value.
- 5.4.2.8 The Estimator shall be verified by running multiple trials with randomized noise and comparing the spread of estimation errors to the reported uncertainty to confirm correspondence within three standard deviations.
- 5.4.2.9 The Estimator shall be verified by mounting sensors in different known orientations and confirming that the estimated attitude and derived quantities correctly reflect the new orientations.
- 5.4.2.10 The Estimator shall be verified by providing inconsistent sensor data (i.e. conflicting altitude or attitude readings) and confirming that these events are detected and logged as anomalies.

- 5.4.2.11 The Estimator shall be verified by delaying sensor data packets to simulate stale information and confirming that outdated data are excluded from use in state estimation.
- 5.4.2.12 The Estimator shall be verified by examining output data during operation to confirm that every estimate includes a timestamp that matches the time of input data used.
- 5.4.2.13 The Estimator shall be verified by providing various combinations of sensor measurements (i.e. IMU only, IMU + GPS, IMU + barometer) and confirming that all are processed through a common data pathway to produce consistent state outputs.
- 5.4.2.14 The Estimator shall be verified by collecting state outputs and confirming through comparison against reference transformations that all data conform to a single body frame and a single inertial frame definition.

5.5 Logger Verification

5.5.1 Storage

- 5.5.1.1 Verify support for retrieval by timestamp and event markers.
- 5.5.1.2 Verify persistence of telemetry streams and storage configuration.
- 5.5.1.3 Verify retrieval of stored log files or records by time/index.
- 5.5.1.4 Verify execution within allocated CPU and power budgets.
- 5.5.1.5 Verify performance across expected environmental conditions.
- 5.5.1.6 Verify protection of critical logs and prevention of data loss on faults.
- 5.5.1.7 Verify modular design and clear interfaces.
- 5.5.1.8 Verify compliance with applicable software development standards.

5.5.2 Transmitt

- 5.5.2.1 Verify telemetry prioritization and retransmission.
- 5.5.2.2 Verify handling of selected telemetry streams and transmission policy.
- 5.5.2.3 Verify transmission of telemetry packets via communications link.
- 5.5.2.4 Verify execution within allocated CPU and power budgets.
- 5.5.2.5 Verify performance across expected environmental conditions.
- 5.5.2.6 Verify prioritization of safety/health telemetry under degraded links.
- 5.5.2.7 Verify modular design and clear interfaces.
- 5.5.2.8 Verify compliance with applicable software development standards.

5.6 Verification Methods

Possible verification methods include:

5.6.1 Inspection:

Inspection is a method of verification consisting of investigation, without the use of special laboratory appliances or procedures, to determine compliance with requirements. Inspection is generally nondestructive and includes (but is not limited to) visual examination, manipulation, gauging, and measurement.

5.6.2 Demonstration:

Demonstration is a method of verification that is limited to readily observable functional operation to determine compliance with requirements. This method shall not require the use of special equipment or sophisticated instrumentation.

5.6.3 Analysis:

Analysis is a method of verification, taking the form of the processing of accumulated results and conclusions, intended to provide proof that verification of a requirement has been accomplished. The analytical results may be based on engineering study, compilation or interpretation of existing information, similarity to previously verified requirements, or derived from lower level examinations, tests, demonstrations, or analyses.

5.6.4 Direct Test:

Test is a method of verification that employs technical means, including (but not limited to) the evaluation of functional characteristics by use of special equipment or instrumentation, simulation techniques, and the application of established principles and procedures to determine compliance with requirements.

5.7 Verify Coverage of Stakeholder Requirements

Paragraph Number	Test Type	Tester's Name	Pass/Fail	Date