EECS 495 Progress Report Week 10

1. Progress
   1. This week we wrapped up coding up all the functions of flying the quadrotor. To offset for a small drift, we tried to tune the I gain and set a hard offset to the IMU readings. We also added four buttons on the joystick to manually tune the offset ( + roll offset, - roll offset, + pitch offset, - pitch offset) to make the drone tunable during flight. This tends to solve most of our drifting problems. In the end, we ended up flying it and it's very rewarding to see the little guy fly!
2. Code

See attached.

1. Contribution

We did everything together.