

Do you need help with interpreting the plots? See [here](#).

PX4 Quadrotor

Varundev Sukhil - Freely Technical Challenge

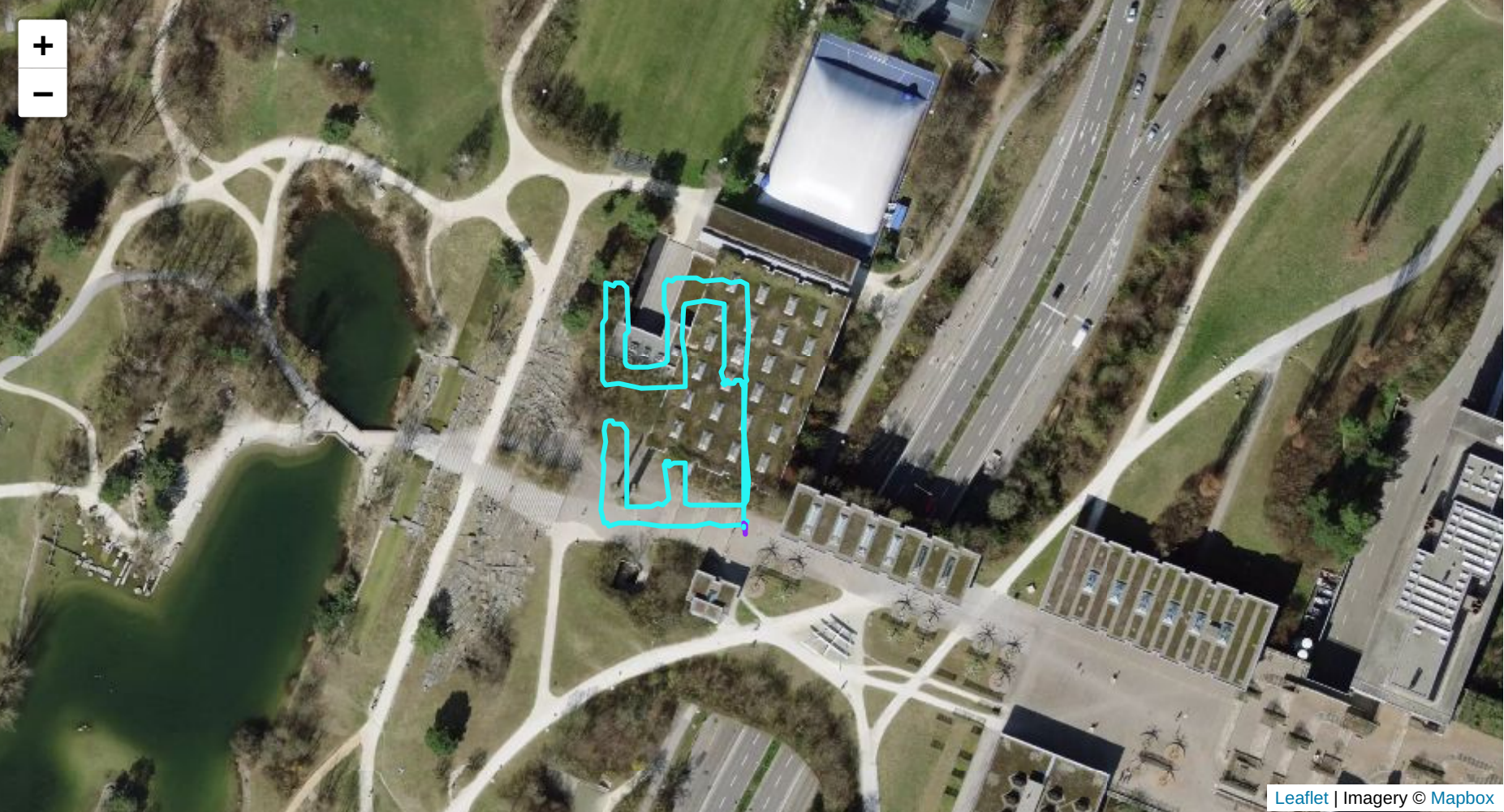
[Open 3D View](#)

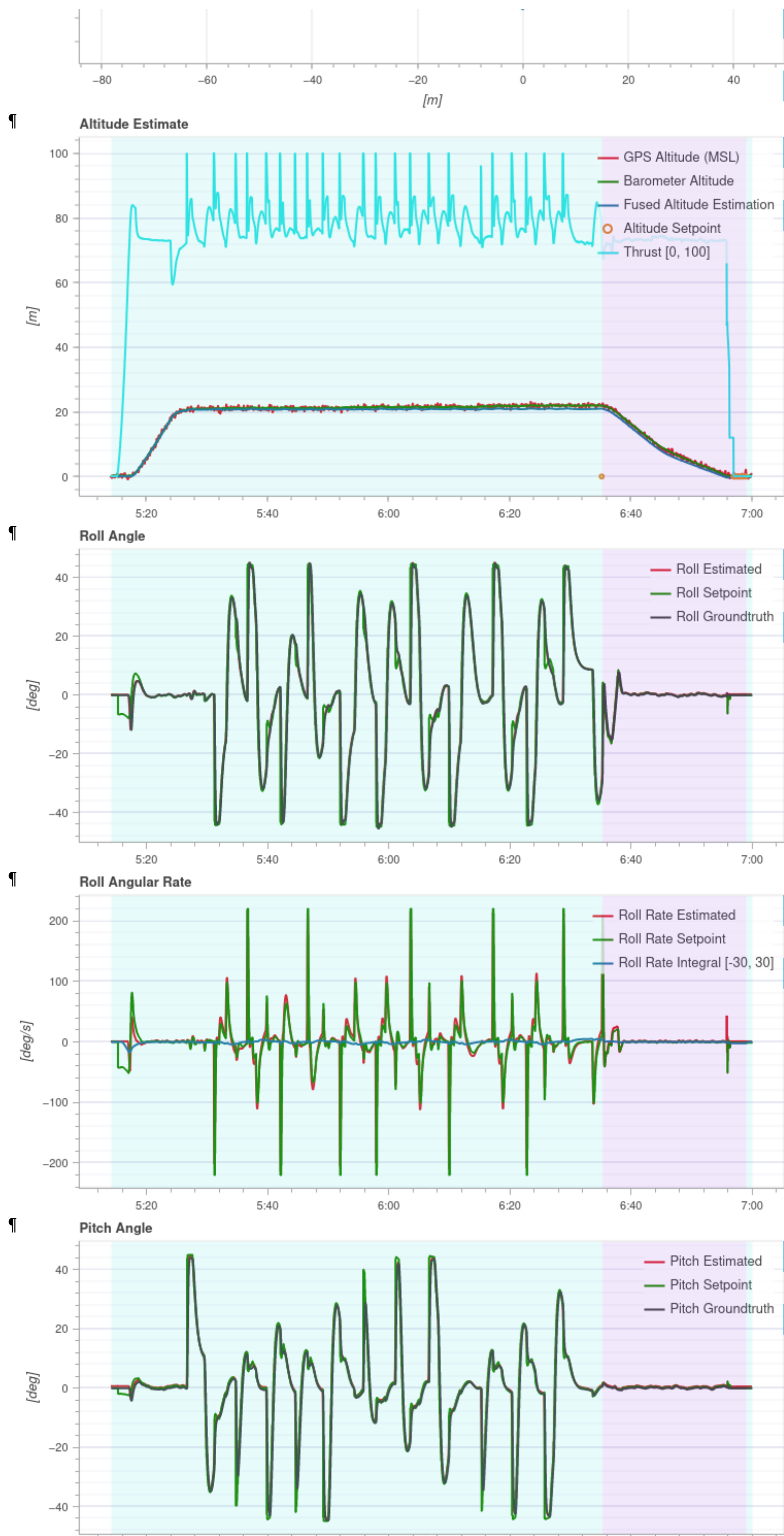
[Open PID Analysis](#)

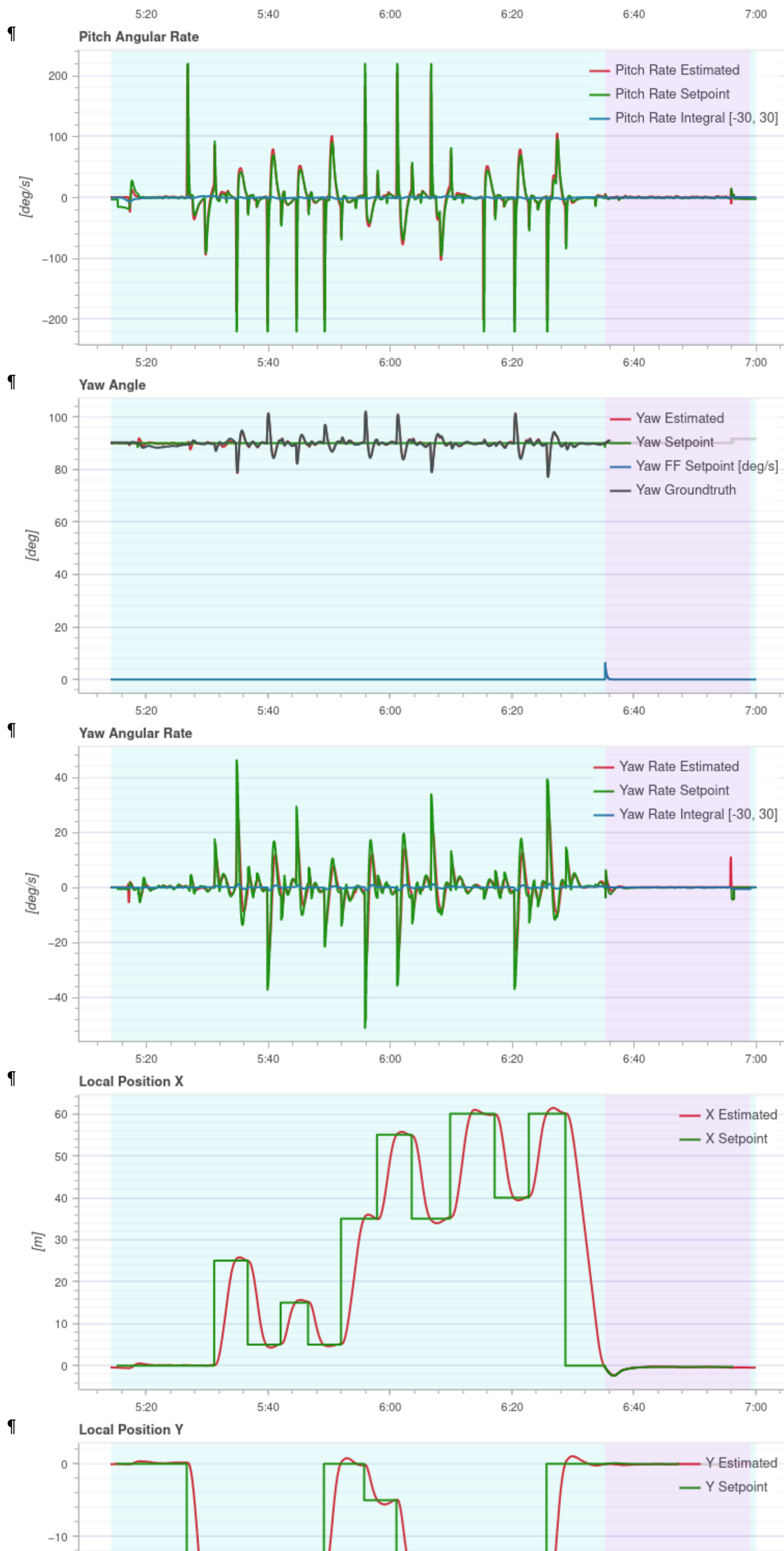
Airframe: Generic Quadcopter
Quadrotor x (4001)
Hardware: PX4_SITL
Software Version: [de9f3a32](#)
branch: main
OS Version: Linux, v6.5.0
Estimator: EKF2
Logging Duration: 0:01:45
Vehicle Life
Flight Time: 33 minutes 43 seconds

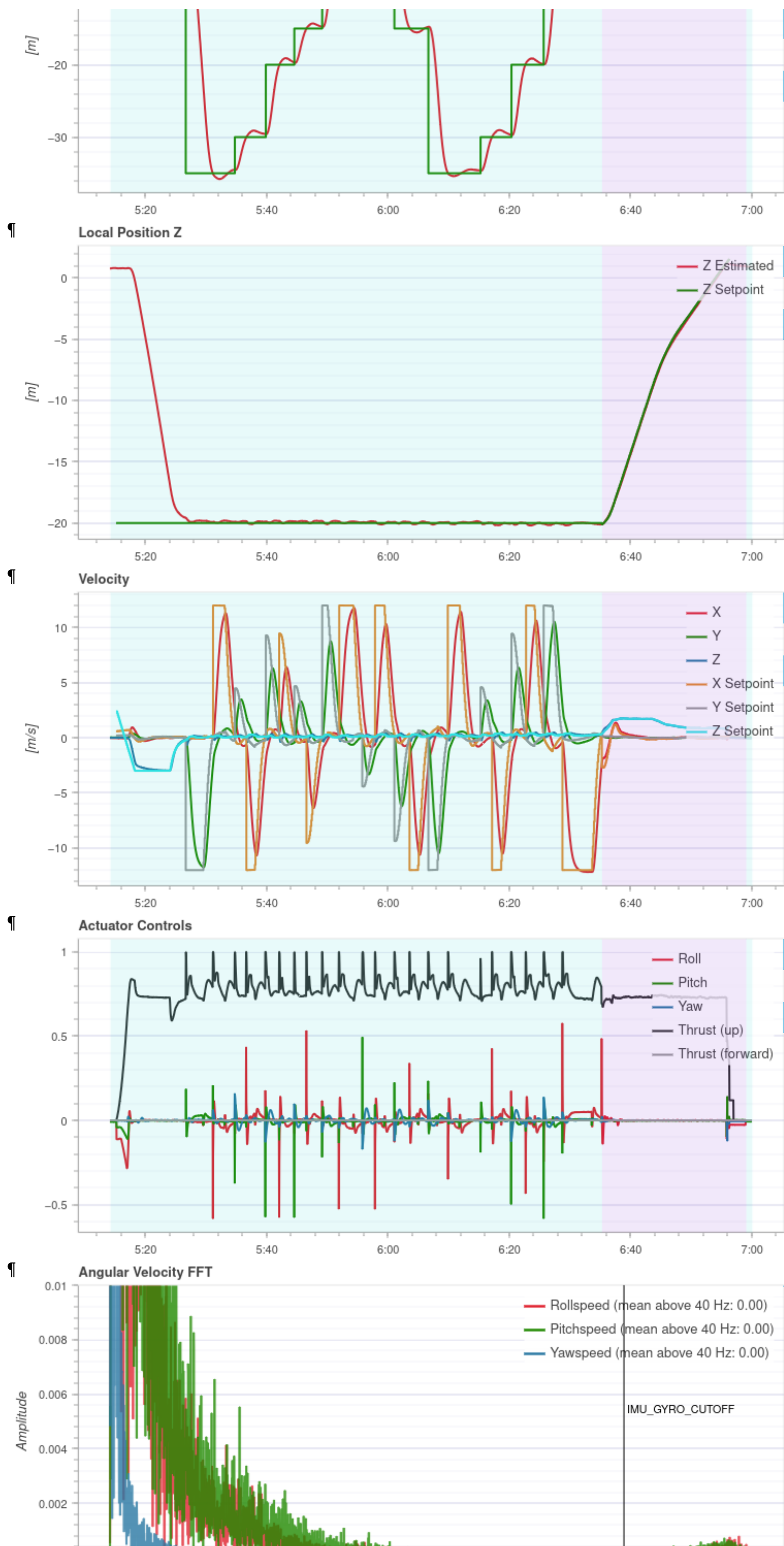
Distance: 453.7 m
Max Altitude Difference: 21 m
Average Speed: 15.7 km/h
Max Speed: 43.9 km/h
Max Speed Horizontal: 43.9 km/h
Max Speed Up: 10.7 km/h
Max Speed Down: 6.3 km/h
Max Tilt Angle: 45.5 deg

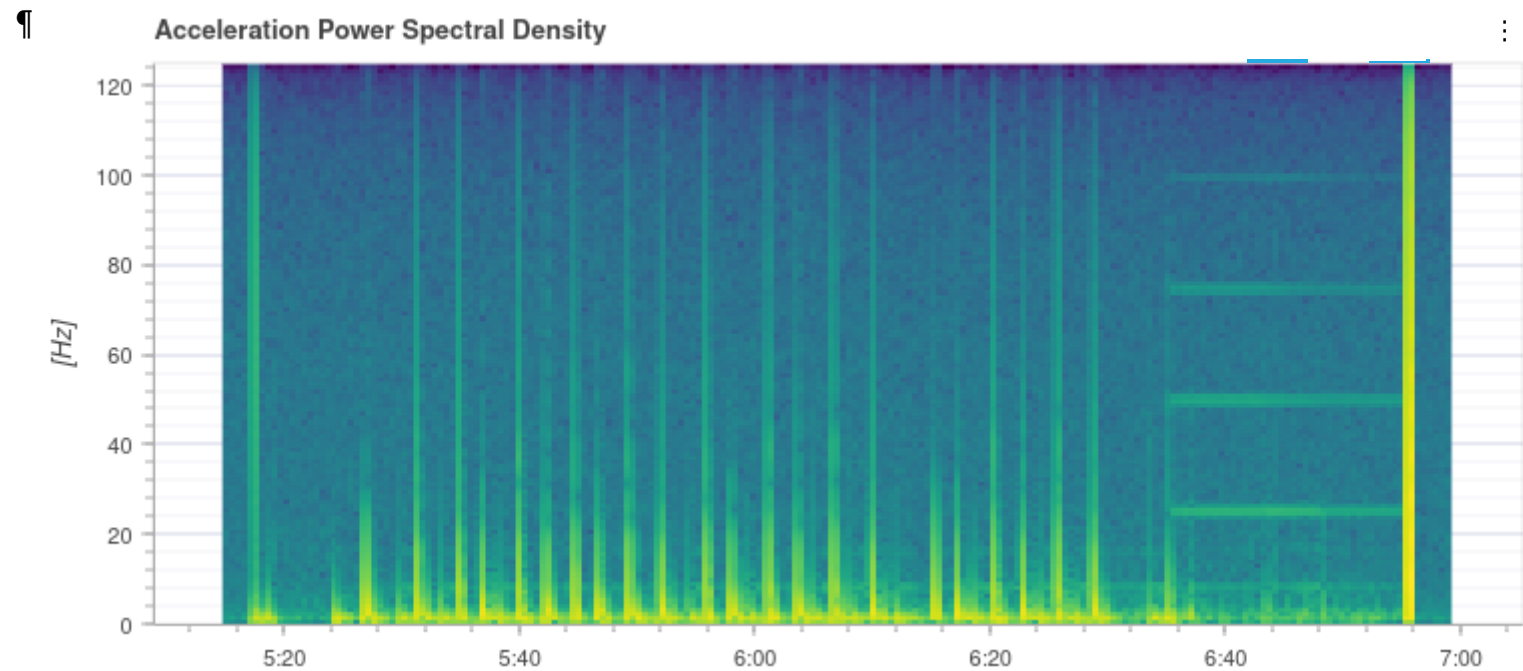
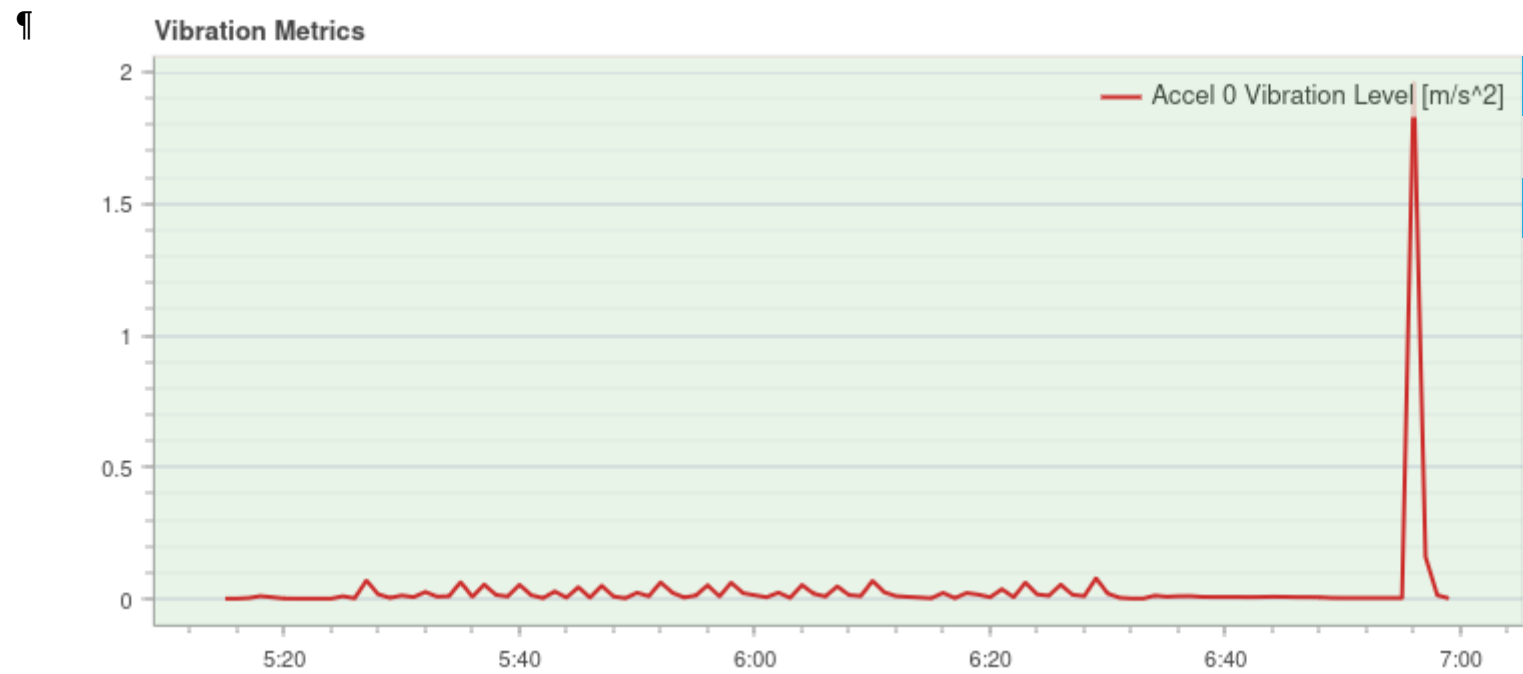
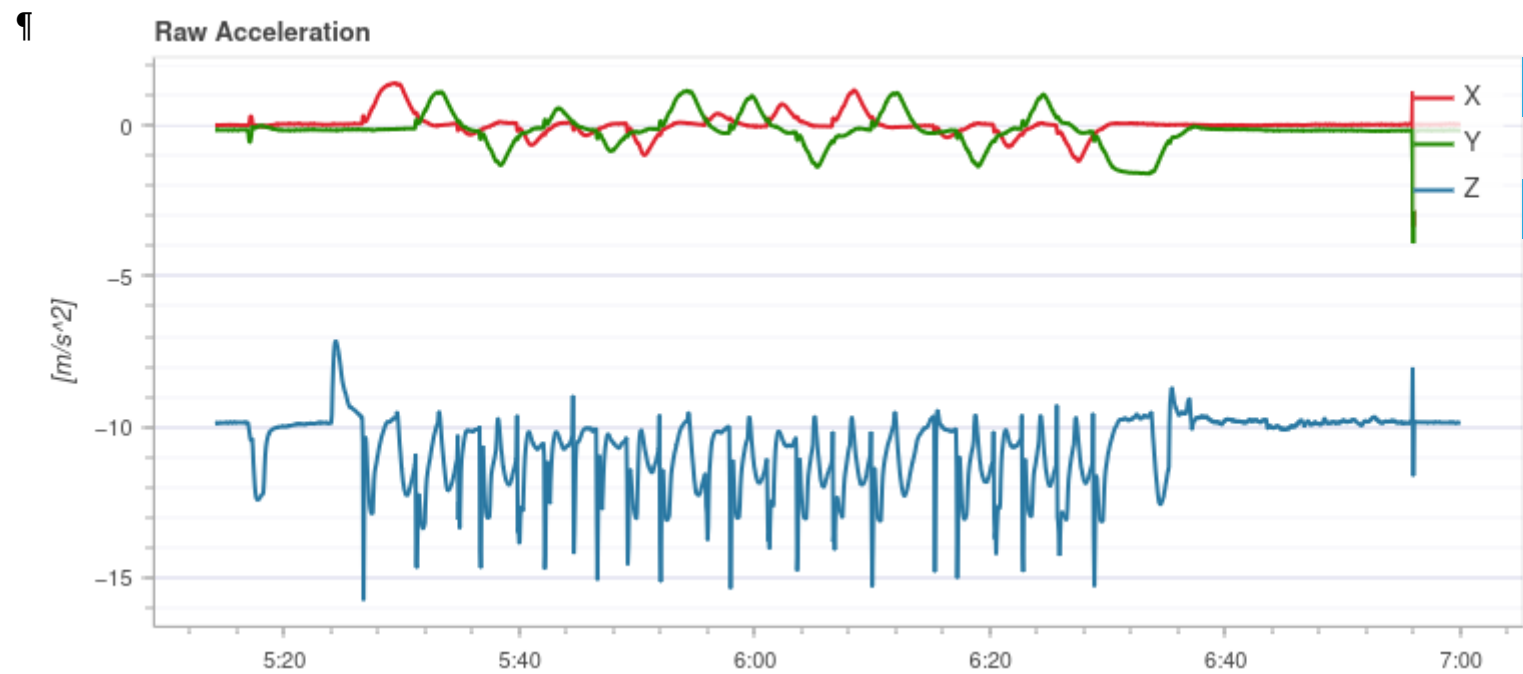
Add a detected error...

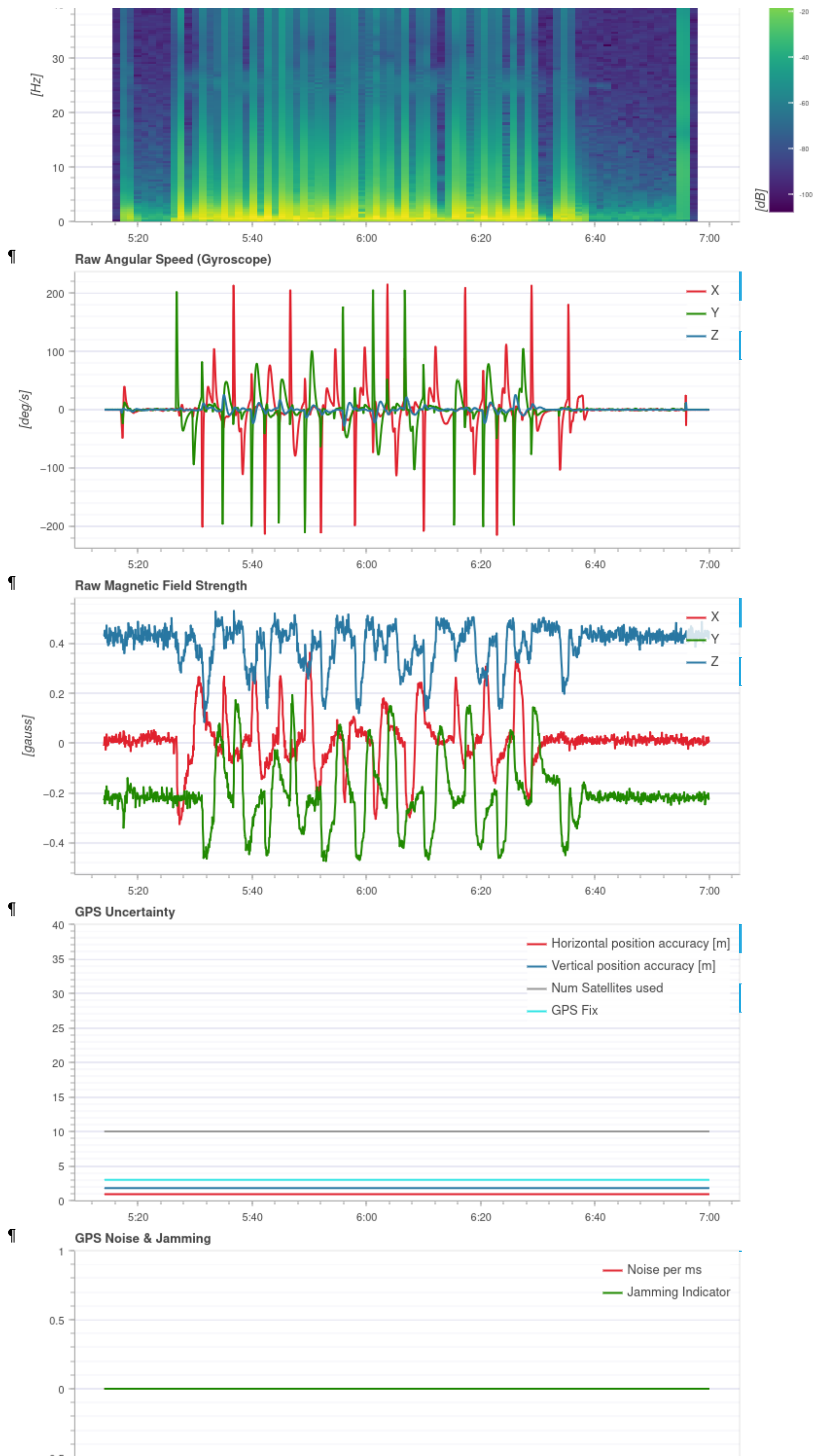


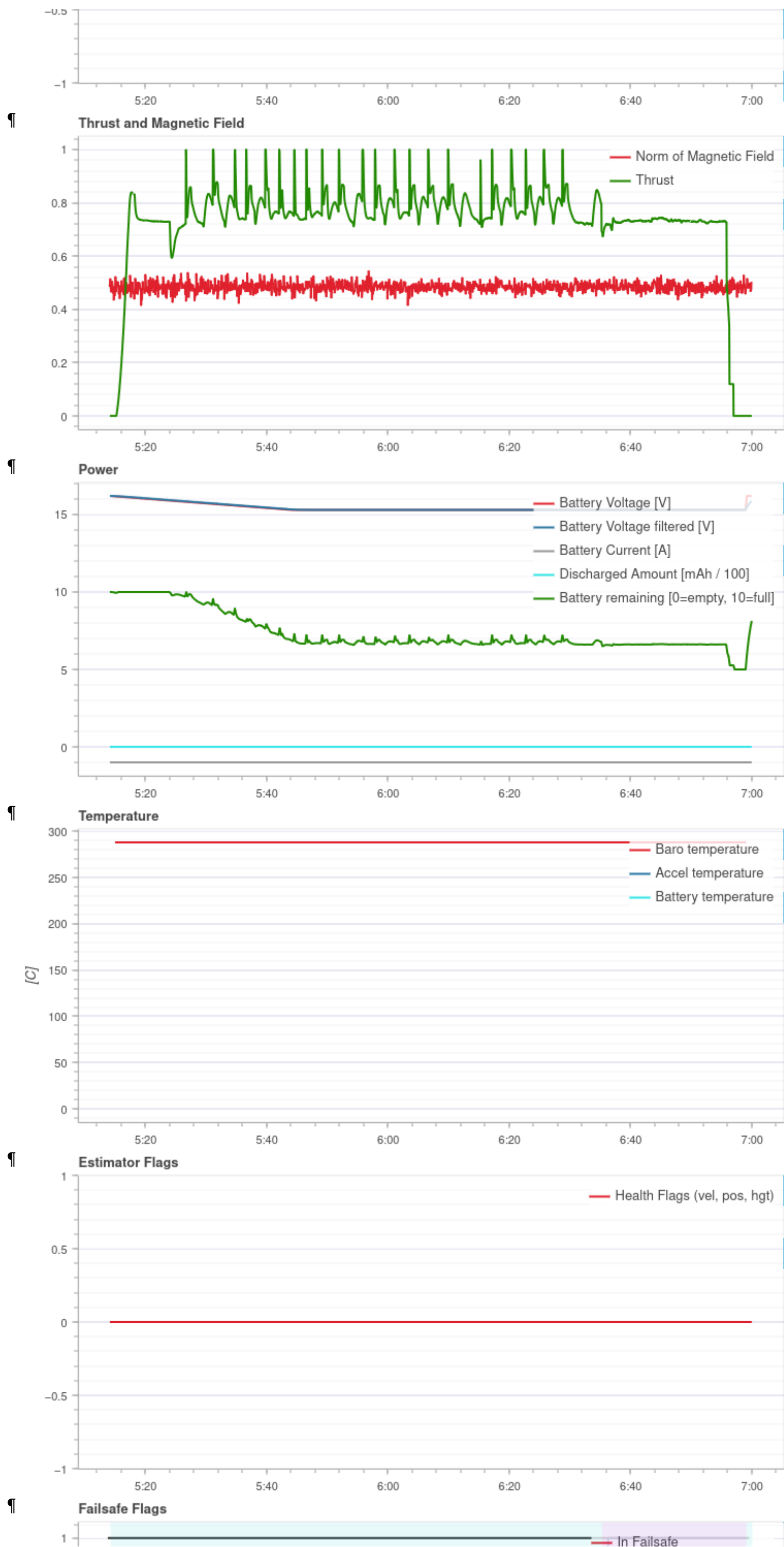


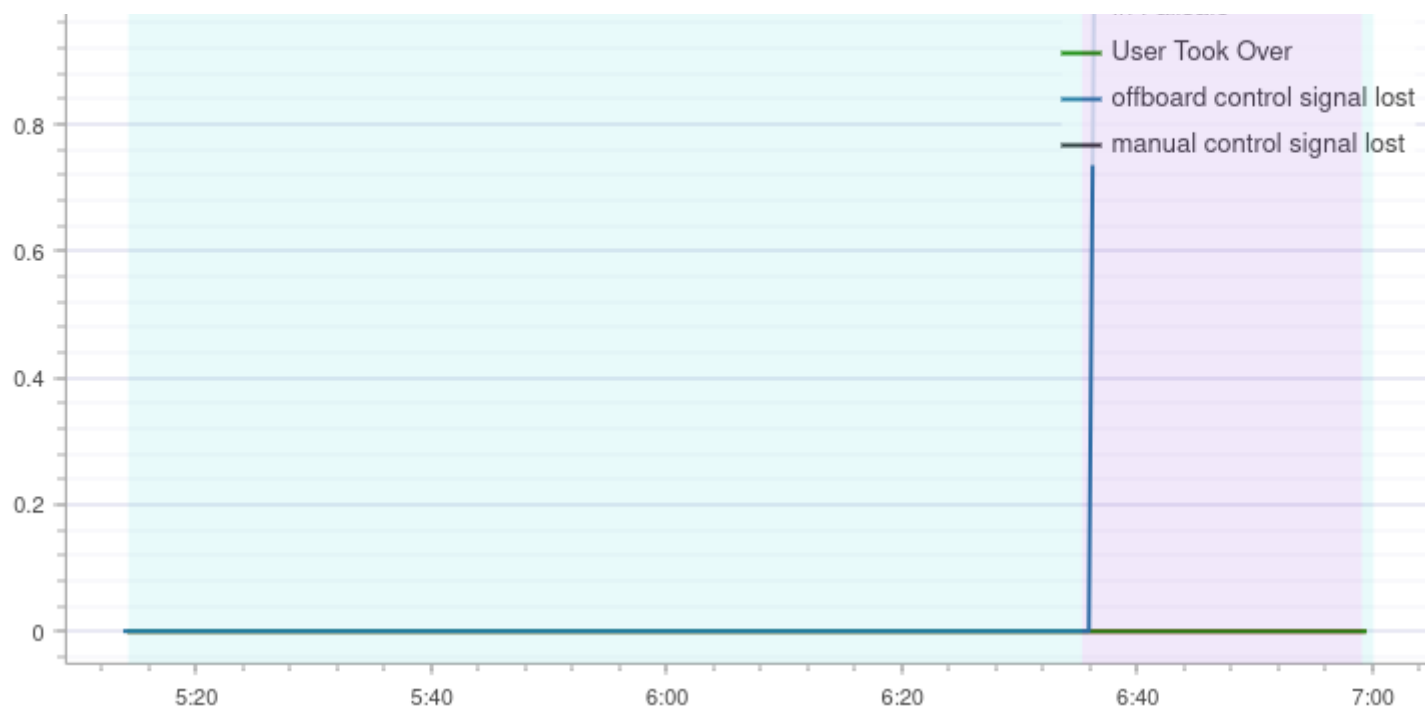




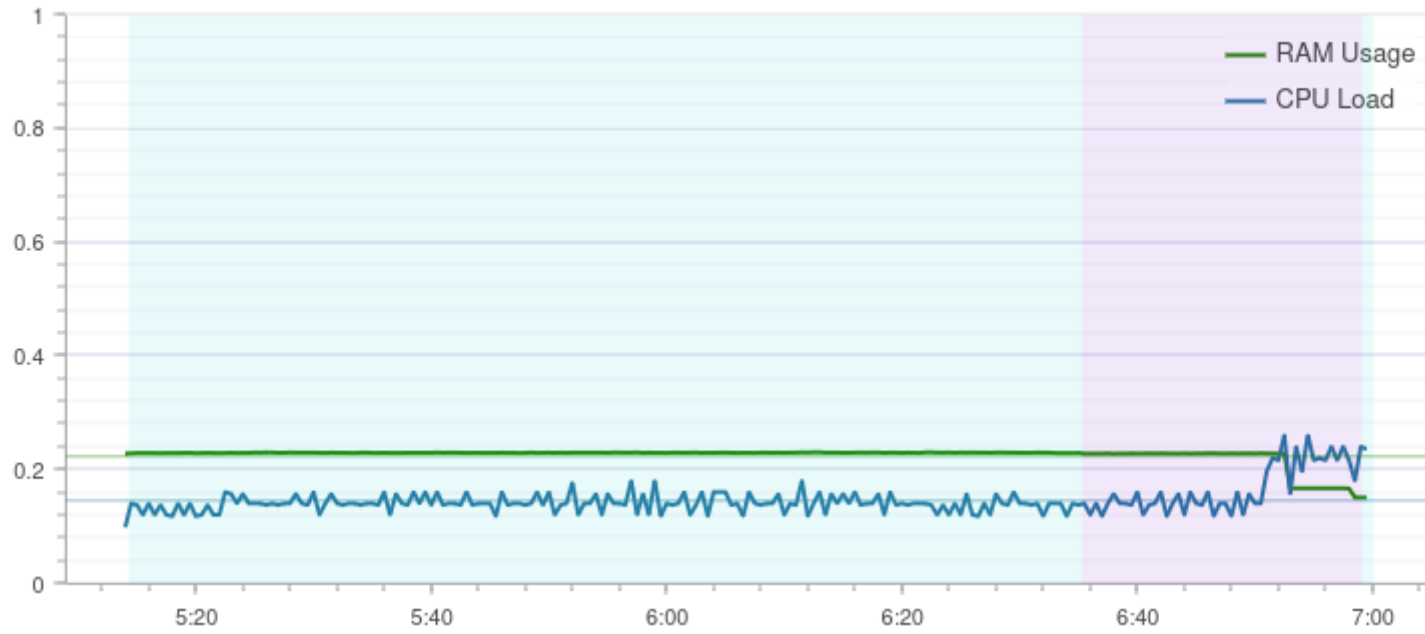




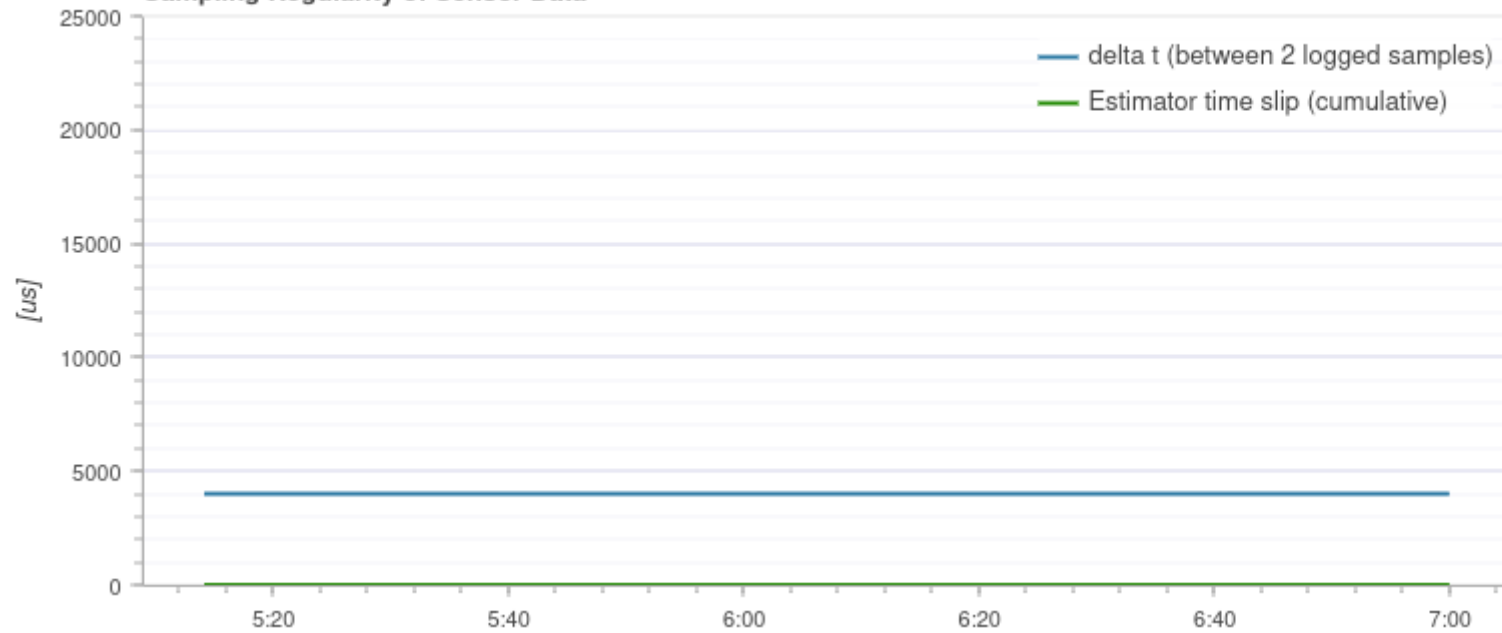




CPU & RAM



Sampling Regularity of Sensor Data



Non-default Parameters
(except RC and sensor calibration)

Logged Messages

Show additional Data

© 2024 PX4 Team. Source on [github](#). Theme by [Bootswatch](#). Plotted with the awesome [bokeh](#) library.