Noise vs Sampling Time

* Variables of note to control for:
  + PID tuning
    - Response time
    - Damping/Robustness
  + Noise
    - Force,
    - Moment
  + Sampling time
* Idealized variables
* Other things to note
  + PID for yaw is removed (we don’t have yaw control)
  + We will assume that our motor outputs perfectly match our PID calculations (yaw/pitch/roll control)

Parameters of interest

* RPY
  + Mean, std of RPY and/or inputs
* Error
* X,y drift