

A drone in everybody's pocket



Bart Remes



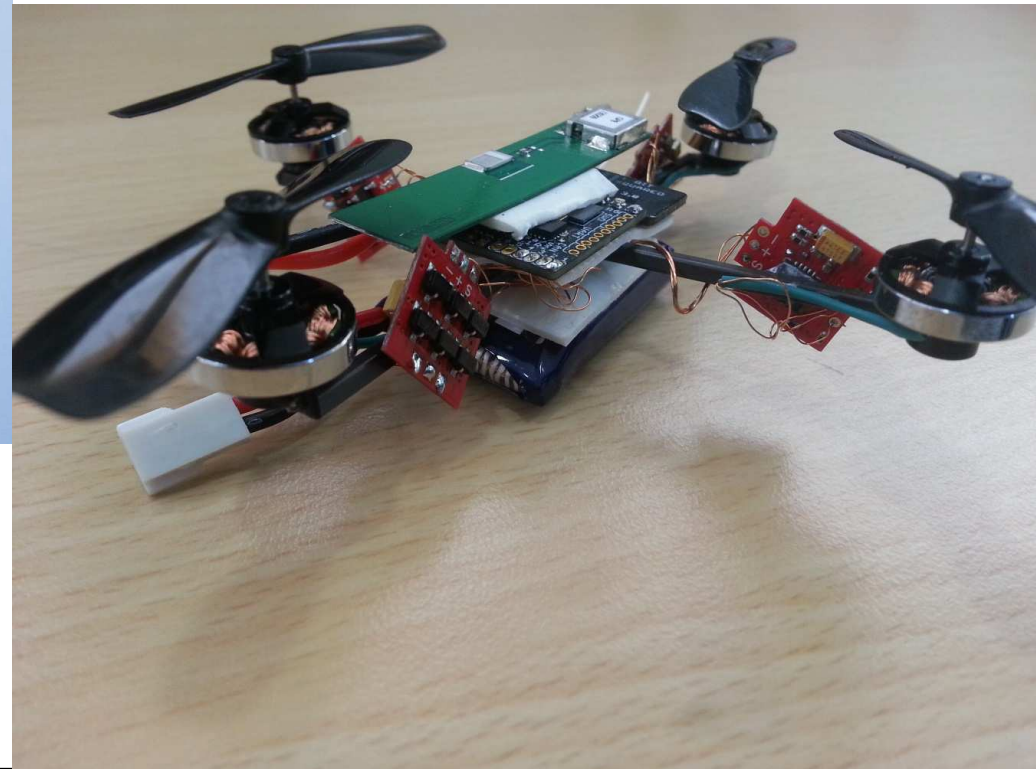
In 2013





www.enac.fr

www.mavlab.lr.tudelft.nl



Properties Lisa S

<http://paparazziuav.org/>

Processing:

- 72MHz 32bit ARM Cortex M3 MCU with 16KB RAM and 512KB Flash

Sensing:

- 3-axis accelerometers, gyros, and magnetometer
- barometer
- uBlox GPS

Communication:

SuperbitRF



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Brian Emfinger

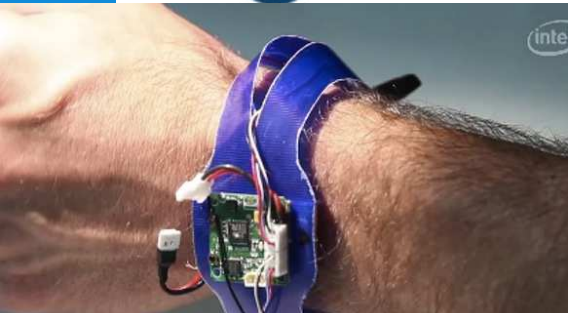
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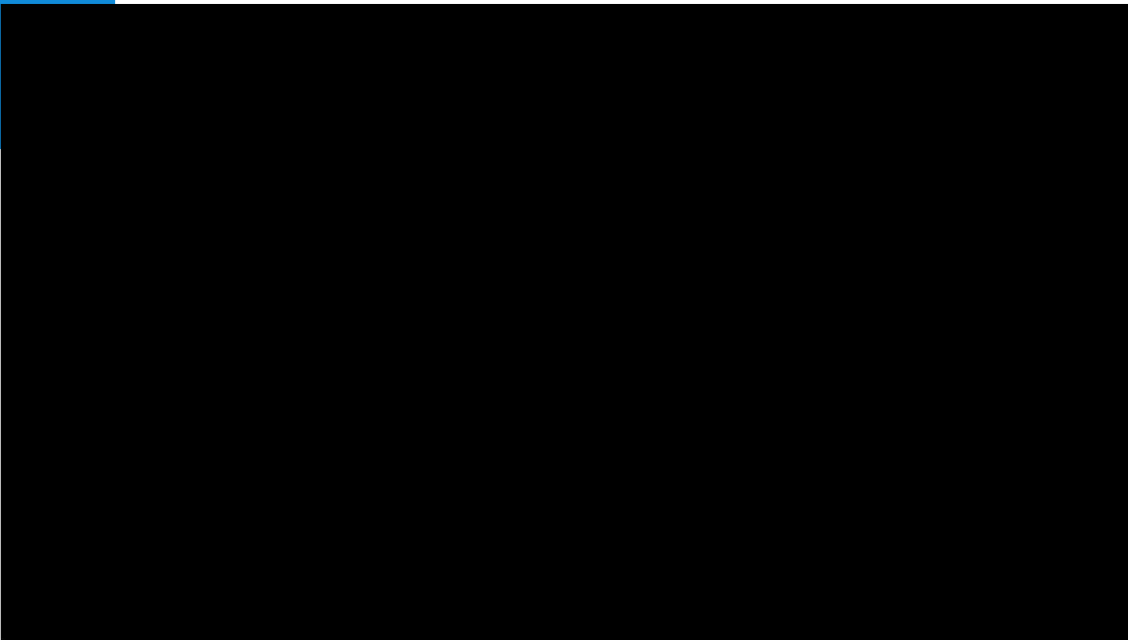
mavlab.ir.tudelft.nl

KICKSTARTER



flyzano.com





<http://paparazziuav.org/>

DelFly Introduction

- Evolved during the last 10 years
 - **September 2005** : DelFly I
=> 40cm span
 - **August 2006** : DelFly II
=> 28cm span
 - **July 2008** : DelFly Micro
=> 10cm span
 - **June 2010**: Autonomous
=> using camera and autopilot
 - **... 2015** Tail less
=> controlled only by wing deformation



DelFly Components

Battery



3.0 gr.

High
power

Receiver &
Actuators



0.9 + 2.3 gr.

Fast data link
smooth control

Motor &
Controller



1.5 + 1.0 gr.

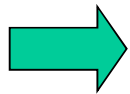
High efficiency
High power

Camera &
Transmitter



1.0 + 1.3 gr.

Color 380
lines
Low
voltage
5 mW



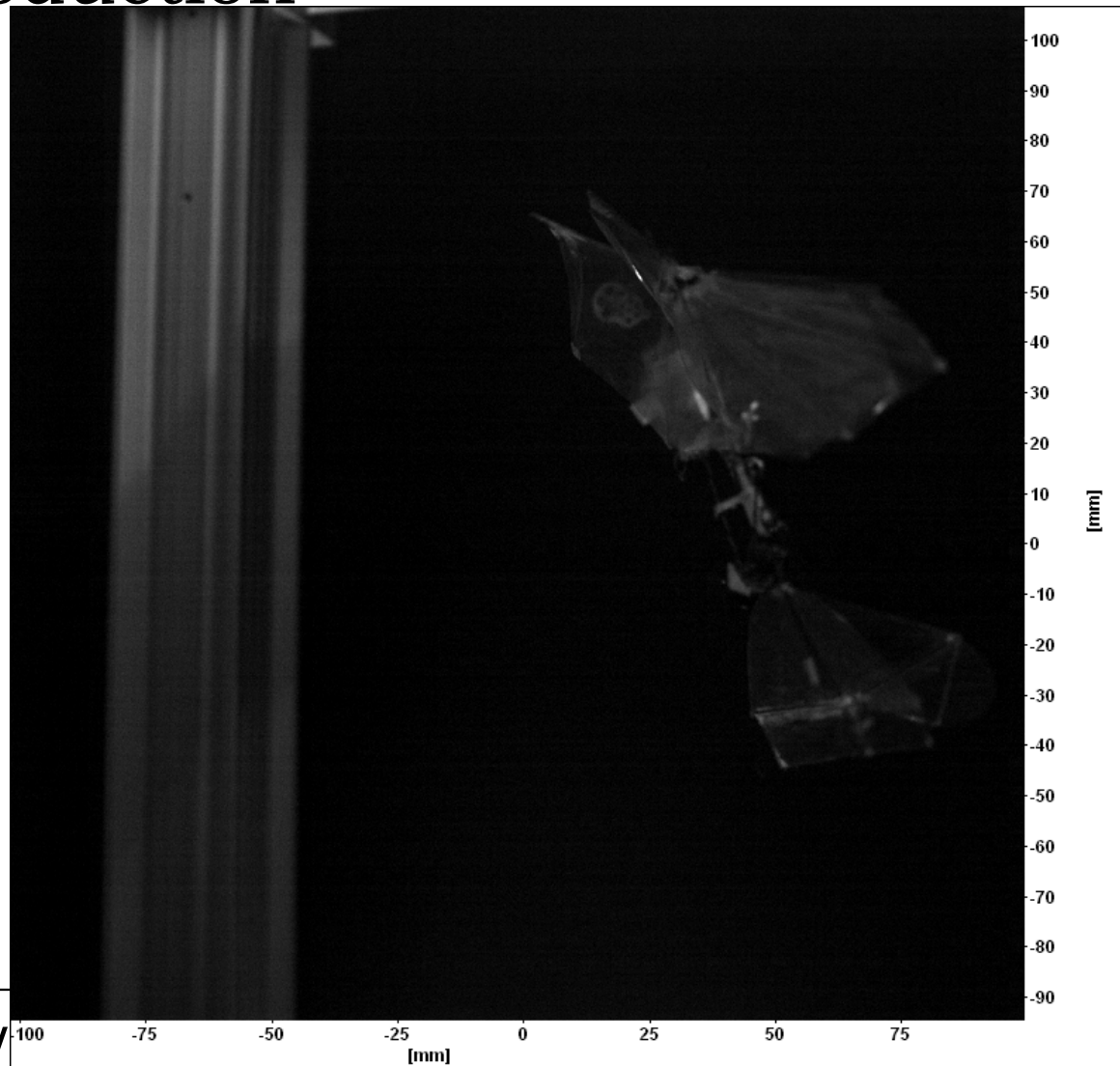
Total weight all components: 11 gram

Total weight of complete MAV: 15 gram

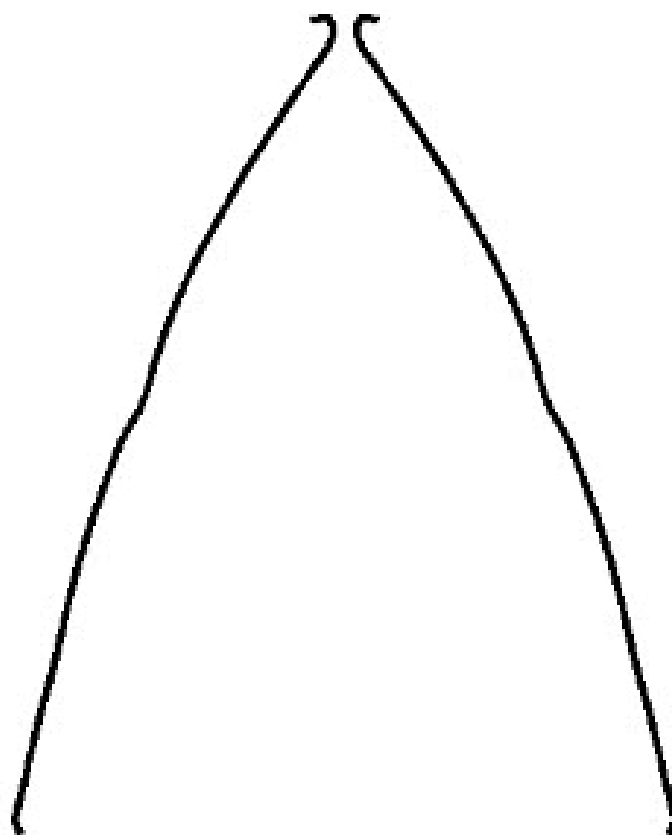
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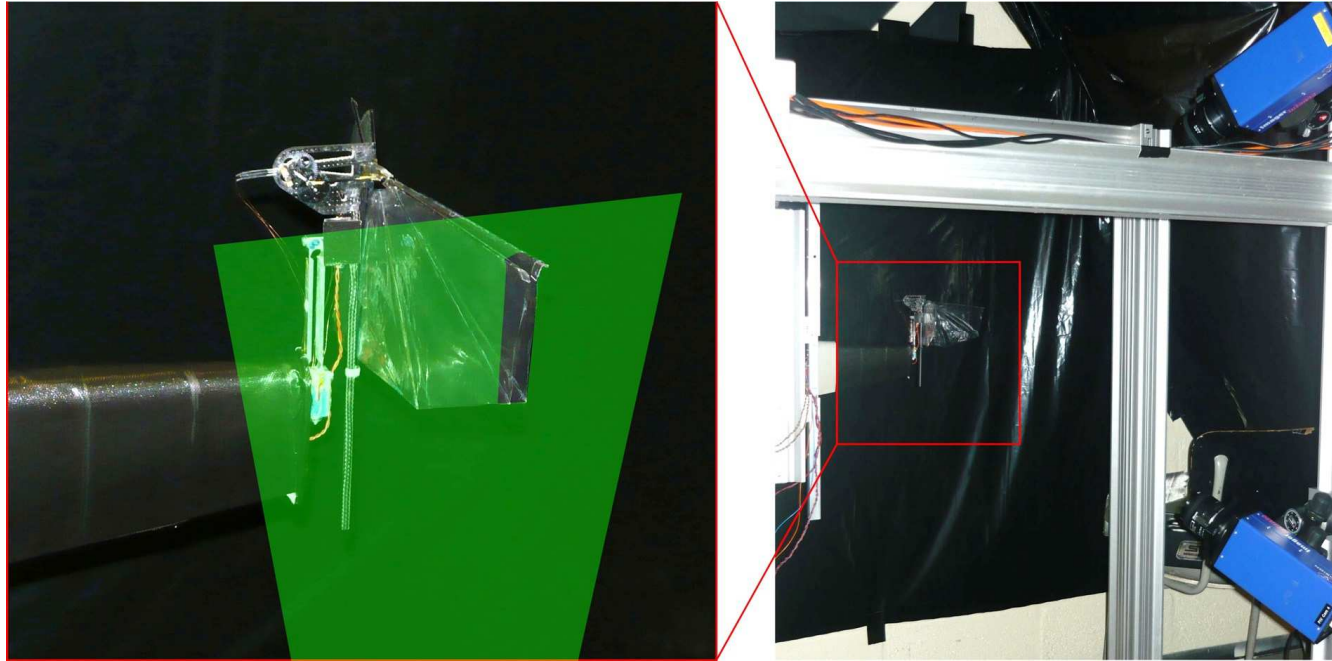
DelFly Introduction



Kristien De Clercq
TU Delft, 2008

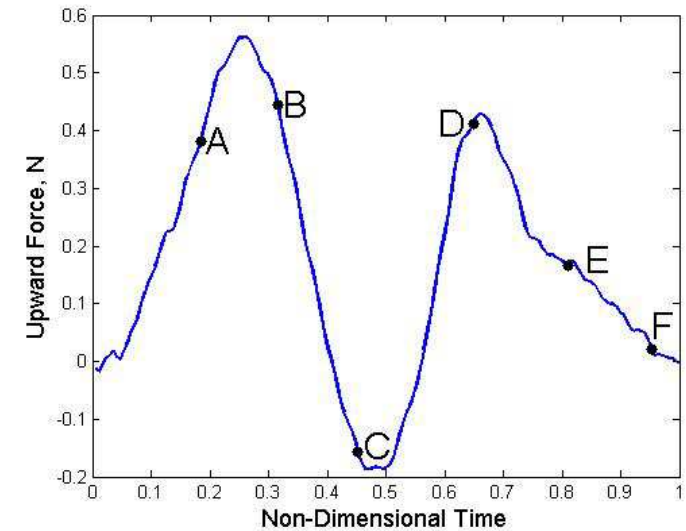
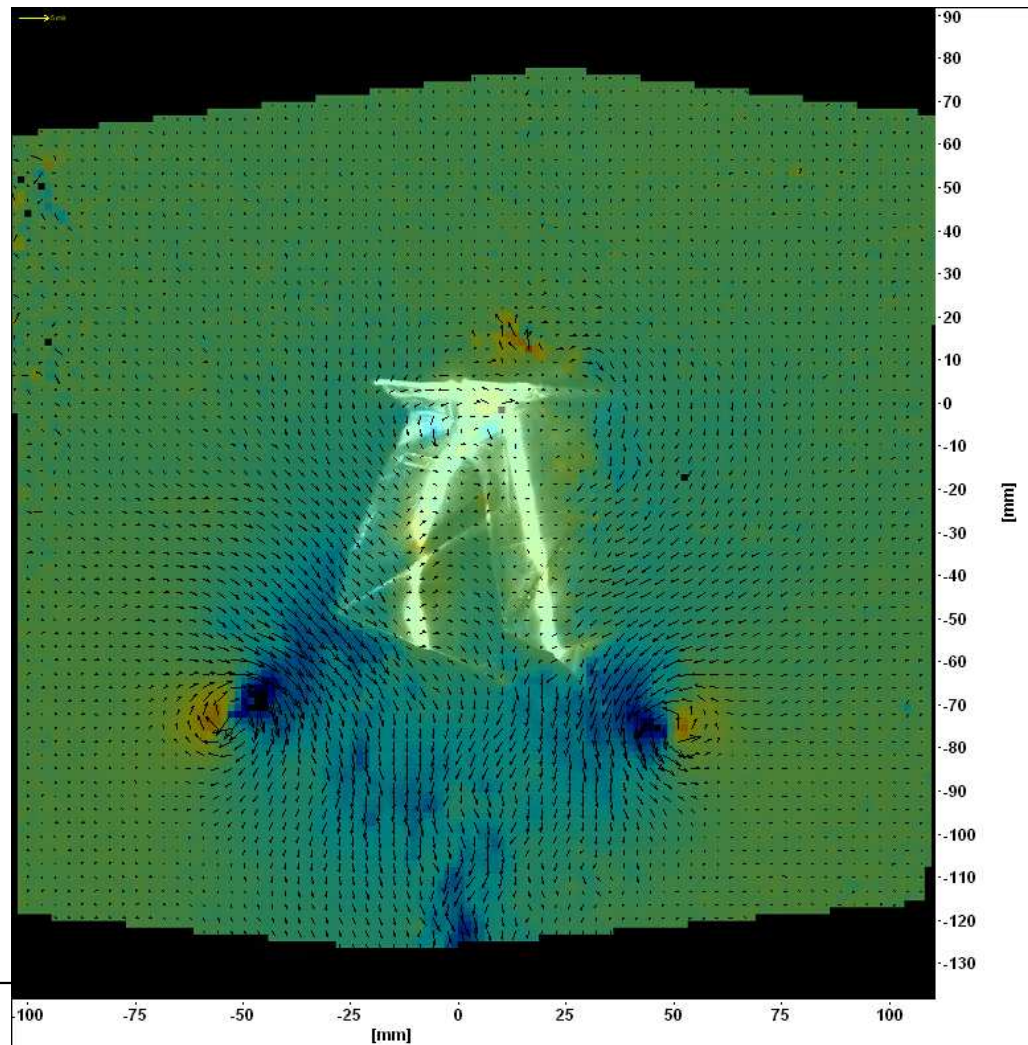


Aerodynamic and Aeroelastic study



Hovering set-up
Stereoscopic PIV

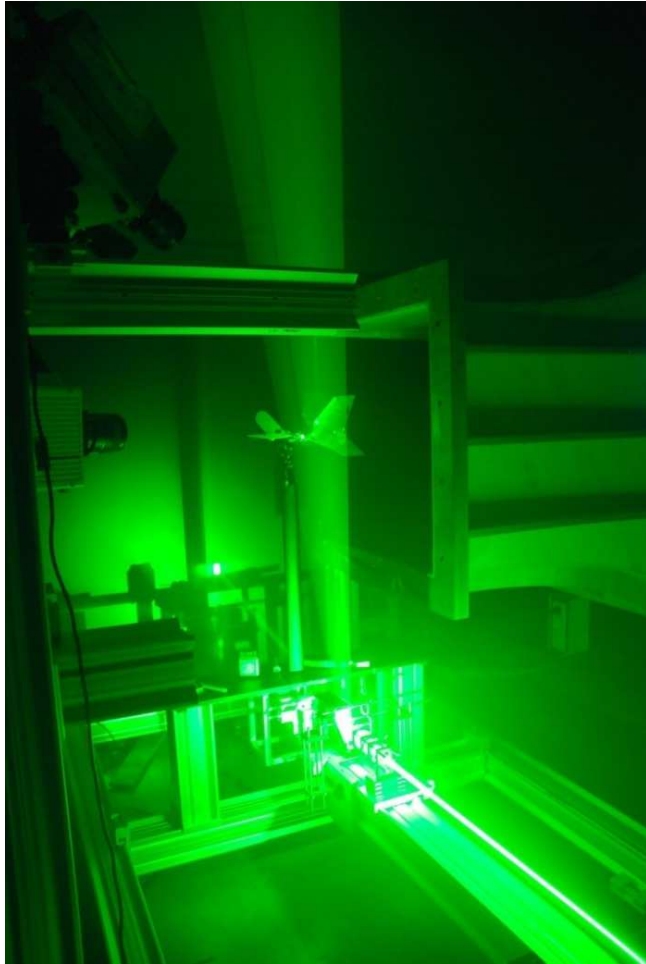
Aerodynamic and Aeroelastic study



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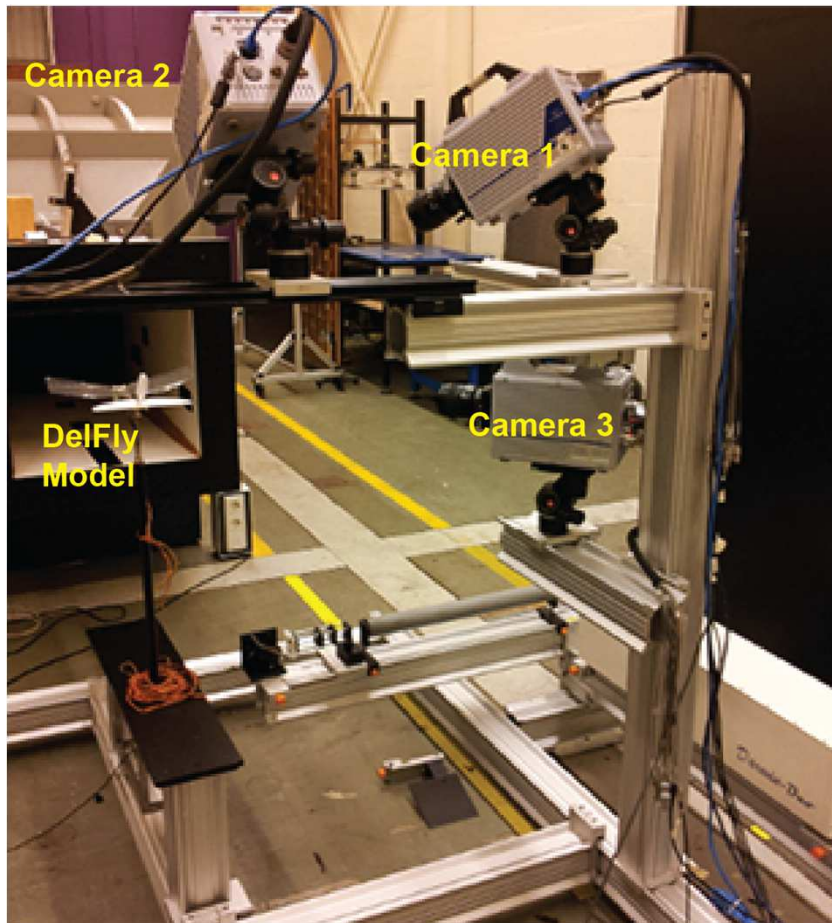
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Wake flow visualization of the DelFly II in forward flight configuration

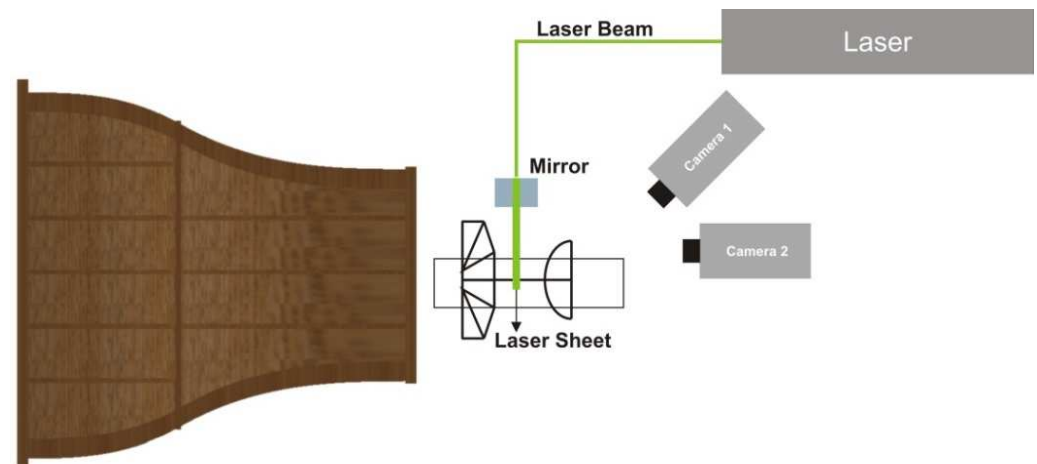


- W wind tunnel with open test section (600×600 mm)
- Full DelFly II model on a 6-component ATI Nano-17 force sensor
- Three high speed cameras (1024×1024 pixels)
- Quantronix Darwin Duo Nd:YLF high speed laser
- Fog of droplets with $1\mu\text{m}$ diameter

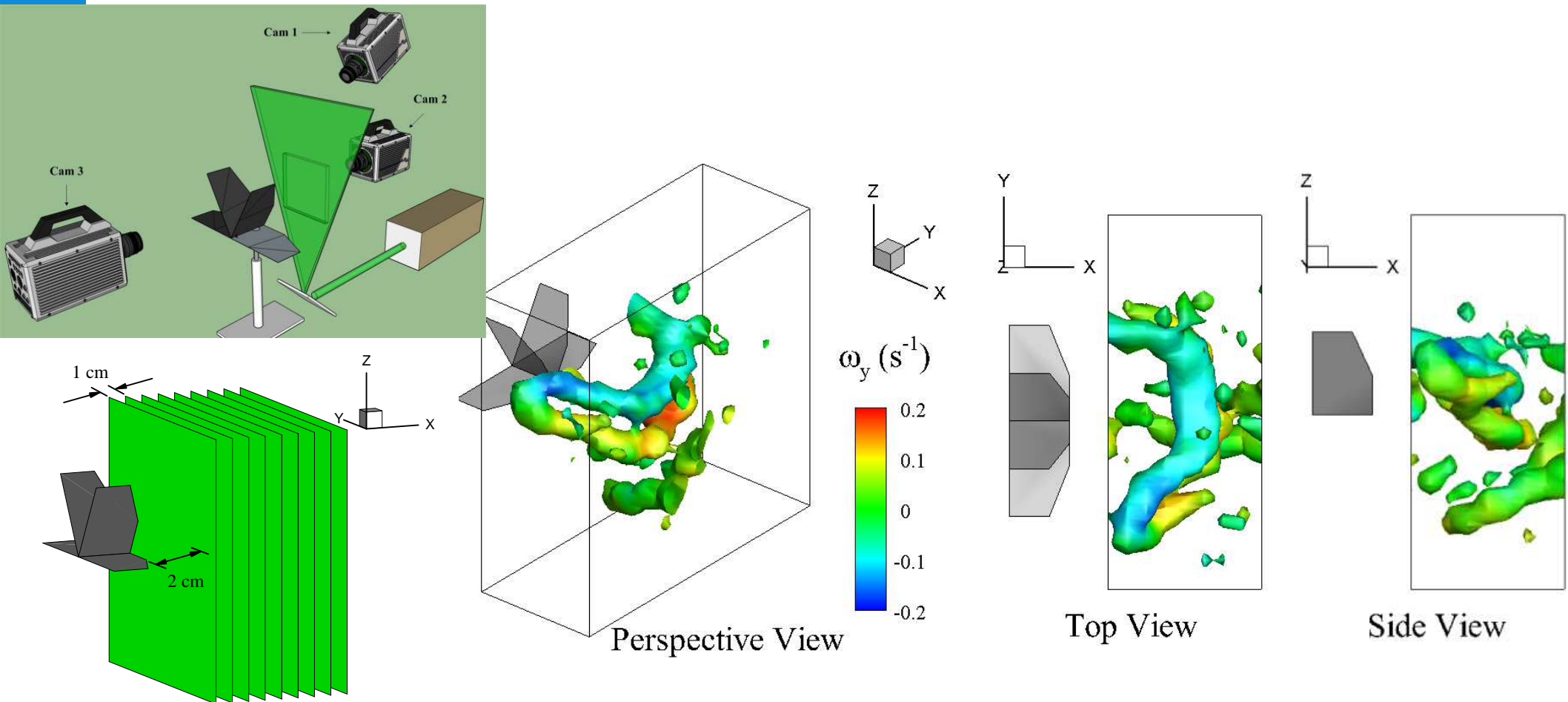
Wake flow visualization of the DelFly II in forward flight configuration



- Measurements at different spanwise planes at 10 mm distance between each other
- Image acquisition at 250 Hz and force measurements at 25 kHz
- Field of view of 200×200 mm
- Synchronization between PIV images, force data and wing stroke via a microcontroller system and a Hall sensor

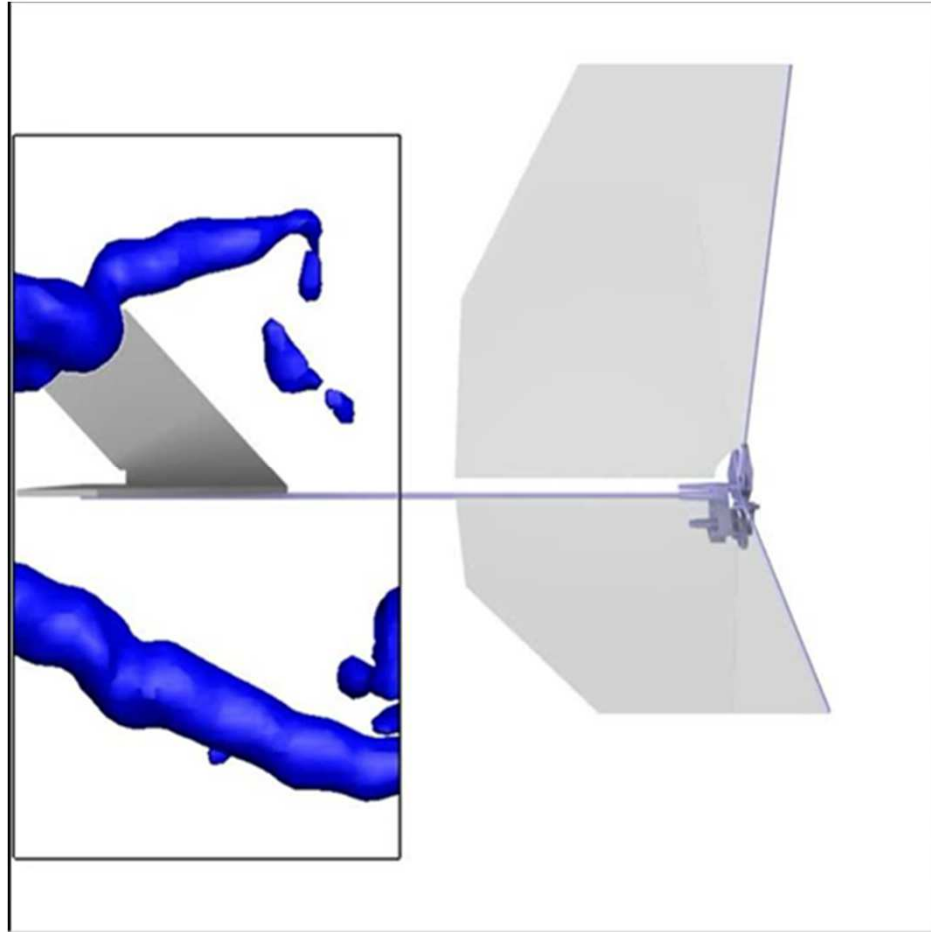
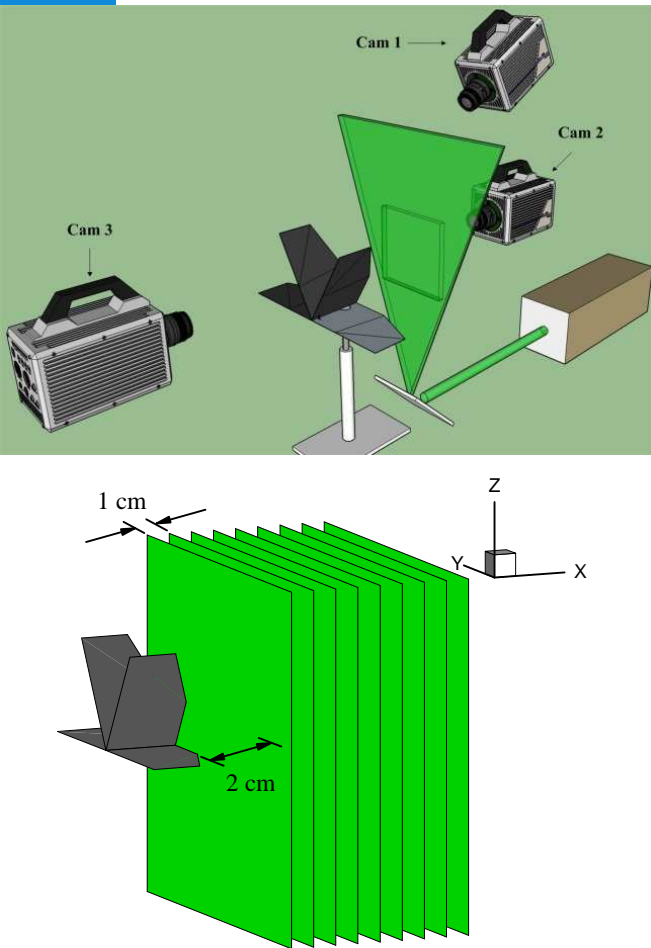


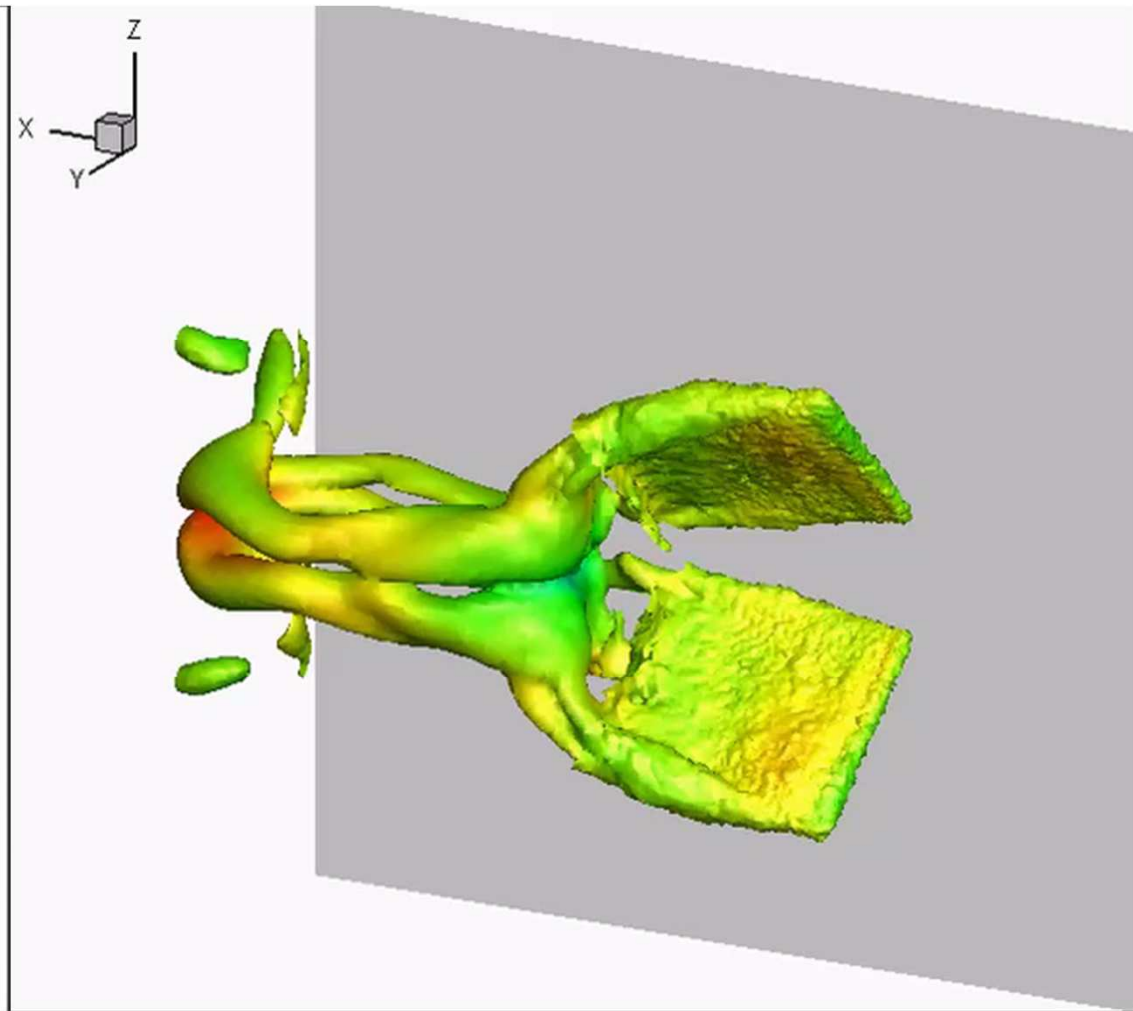
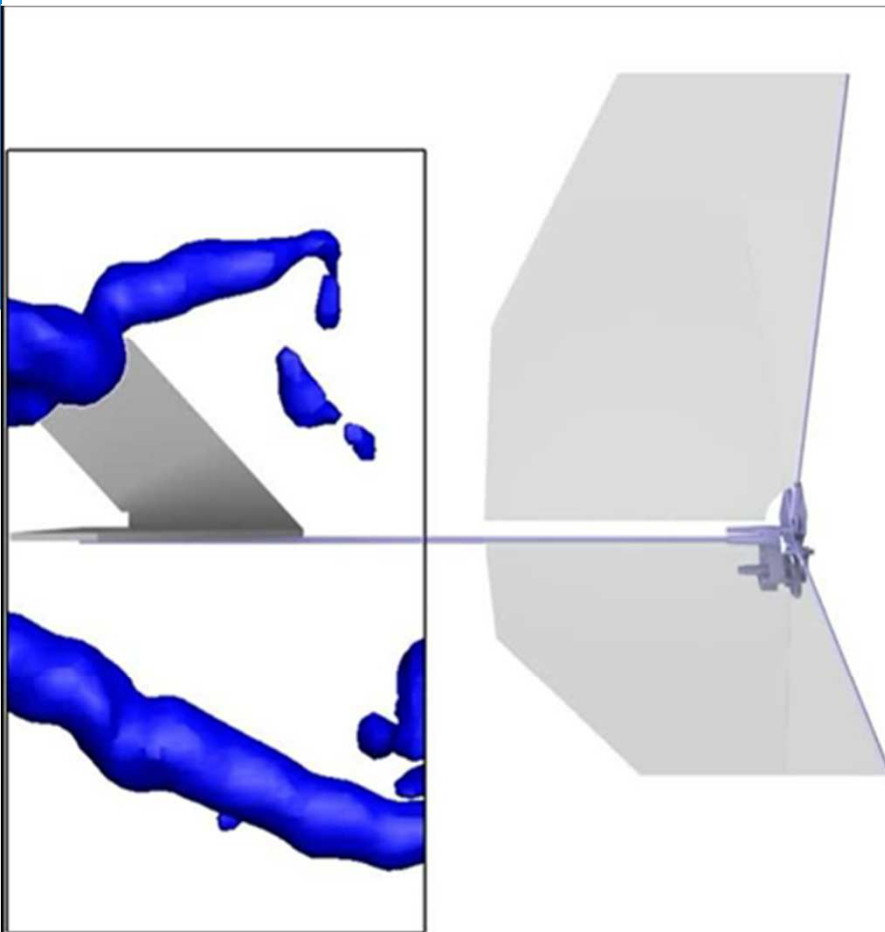
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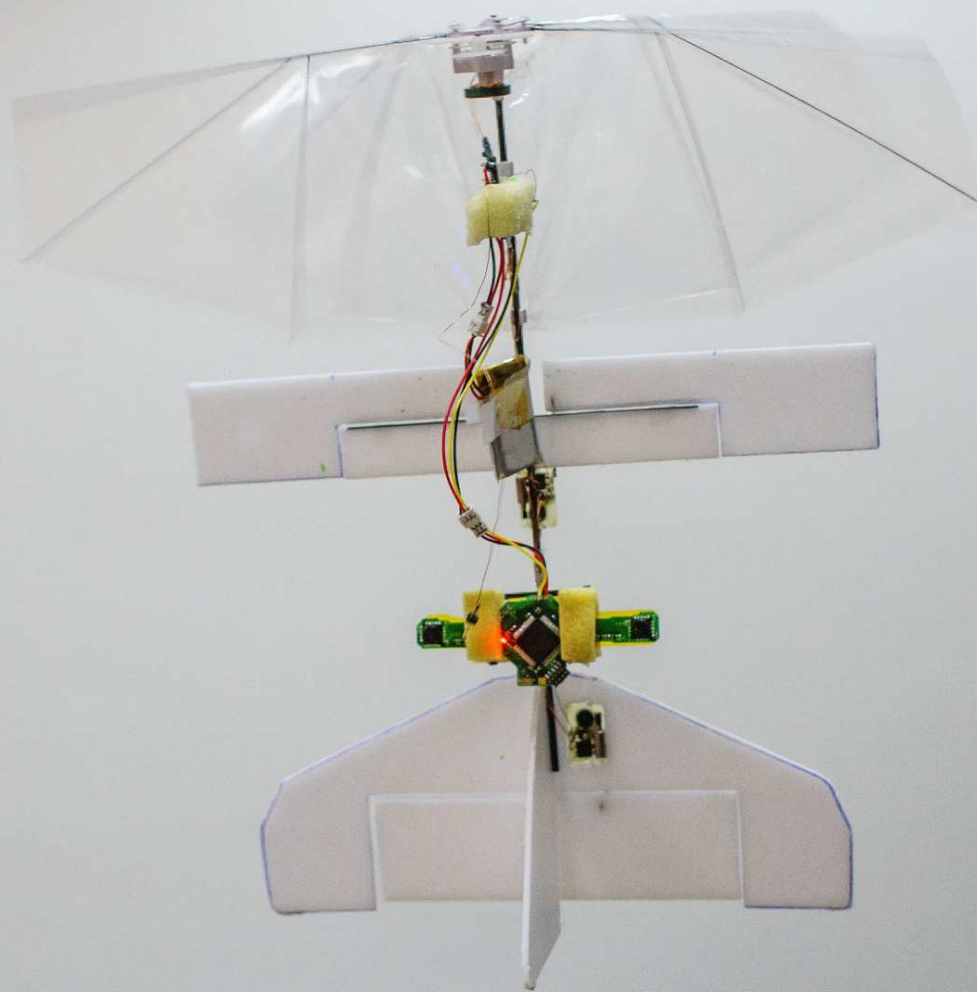


Kriging regression with local error estimate

Wake video



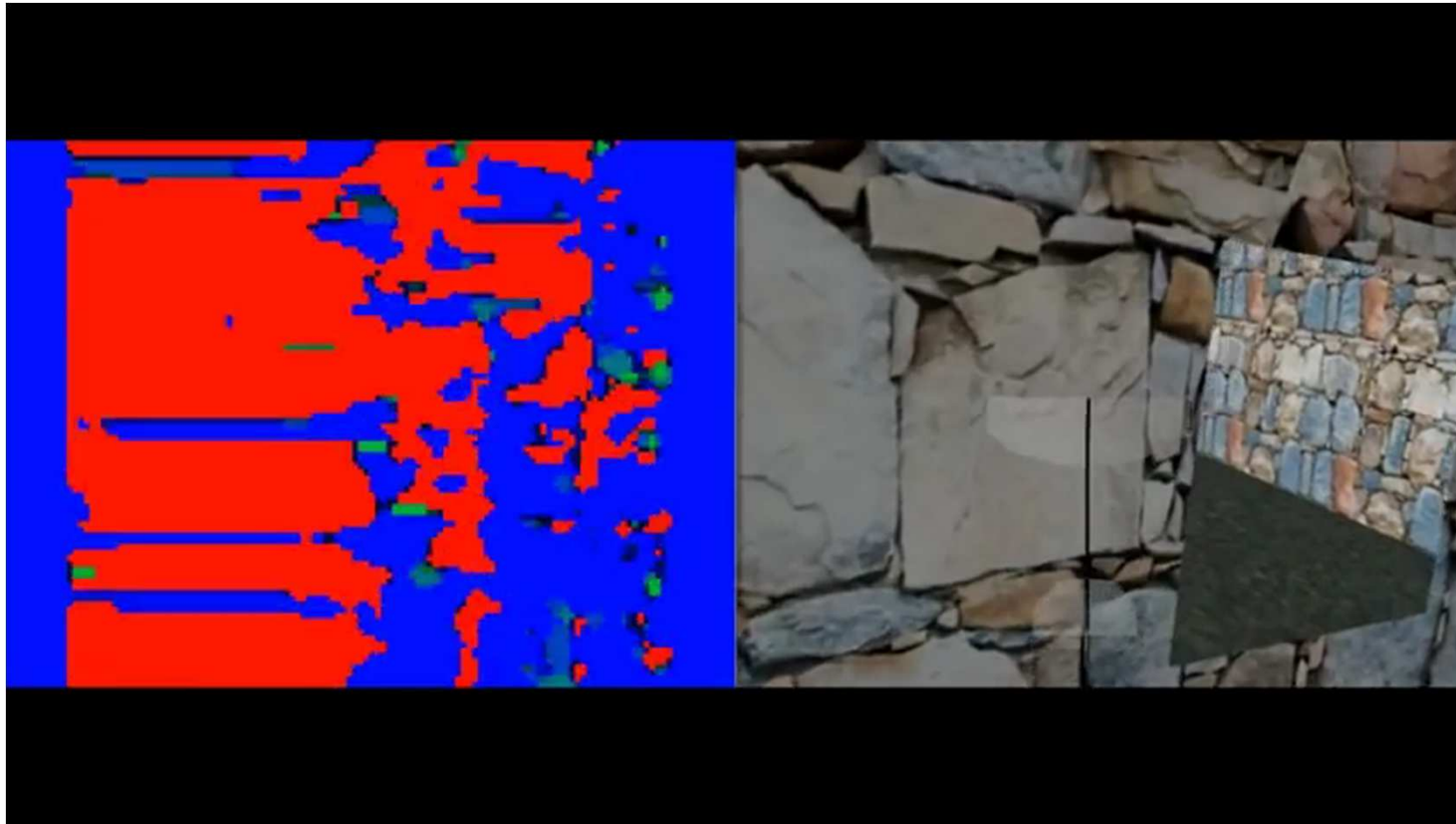


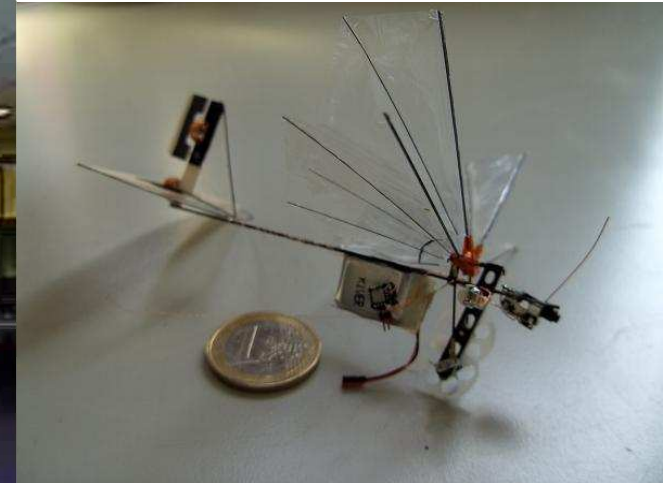


DelFly explorer

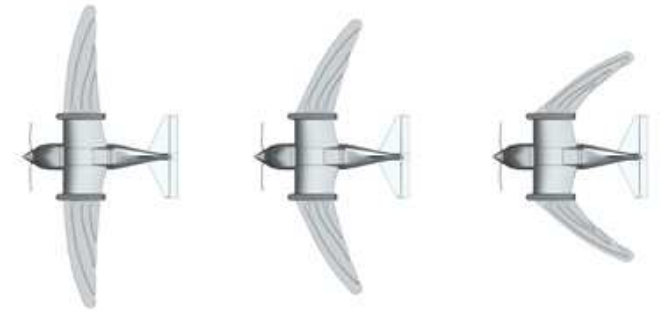


DelFly explorer









MAV LabTM

