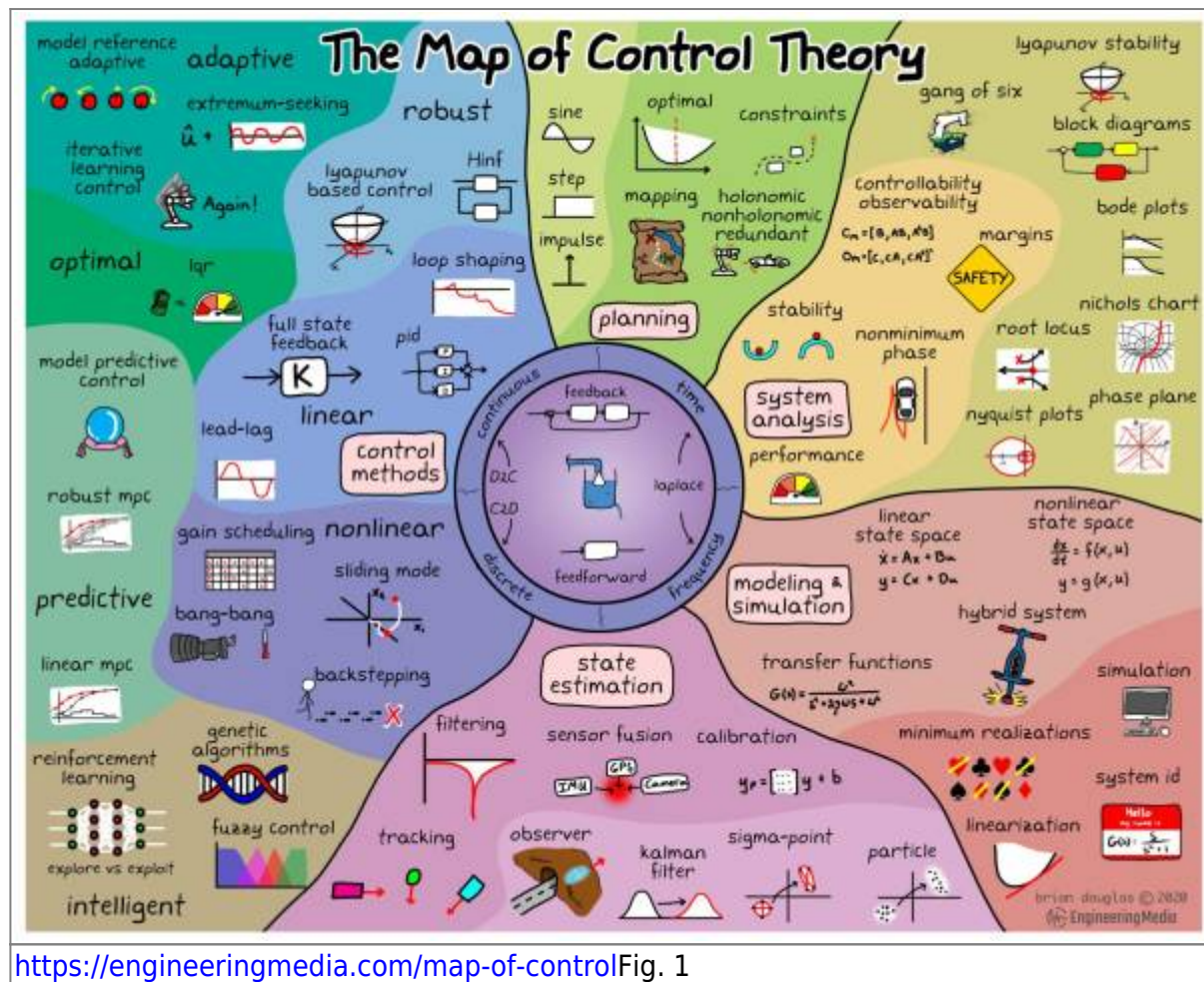


# EMRP2022

## Closed loop control

### PID Control Theory

[https://www.youtube.com/watch?v=wkfEZmsQqiA&list=PLn8PRpmsu08pQBjxYFXSsODEF3Jqmm-y&a\\_b\\_channel=MATLAB](https://www.youtube.com/watch?v=wkfEZmsQqiA&list=PLn8PRpmsu08pQBjxYFXSsODEF3Jqmm-y&a_b_channel=MATLAB)



<https://engineeringmedia.com/map-of-control> Fig. 1

### Inverted Pendulum with PID

#### Optimal control of inverted pendulum system using PID controller, LQR and MPC

<https://iopscience.iop.org/article/10.1088/1757-899X/263/5/052007/pdf>

#### Stabilising an Inverted Pendulum Controller with PID controller

[https://www.matec-conferences.org/articles/mateconf/pdf/2018/11/mateconf\\_eureca2018\\_02009.pdf](https://www.matec-conferences.org/articles/mateconf/pdf/2018/11/mateconf_eureca2018_02009.pdf)

# Control the Ryze Tello Drone from Python

- **tello-pathon** code by Harley Lara: <https://github.com/harleylara/tello-python>
- **RyzeTelloHSRW** code by Ilgar Rasulov (EligoSoftware):  
[https://github.com/eligosoftware/ryzetellohsrw/blob/main/basic\\_follow.py](https://github.com/eligosoftware/ryzetellohsrw/blob/main/basic_follow.py)

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