

Do you need help with interpreting the plots? See here.

PX4 Quadrotor

[Open 3D View](#)

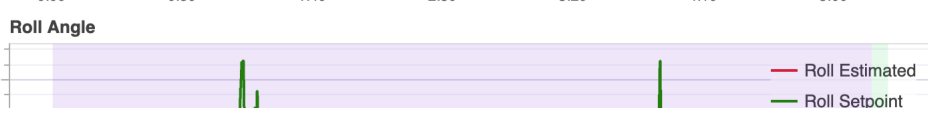
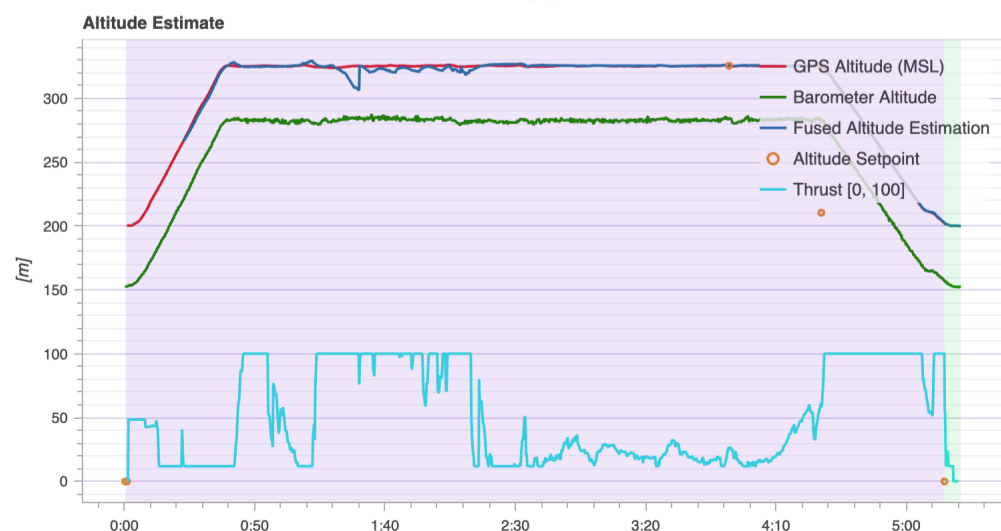
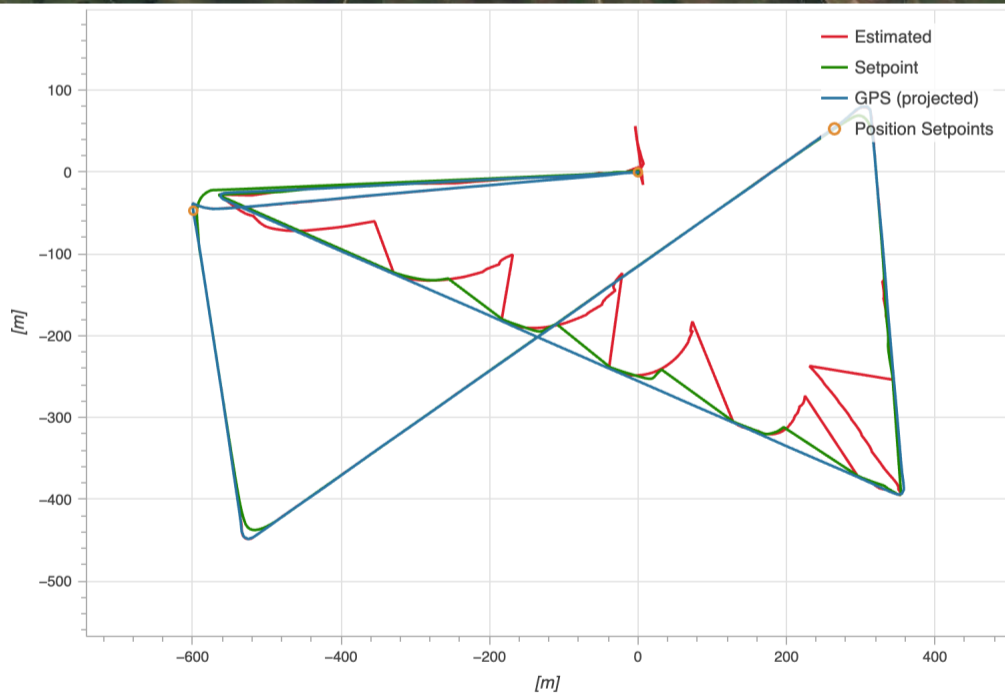
[Open PID Analysis](#)

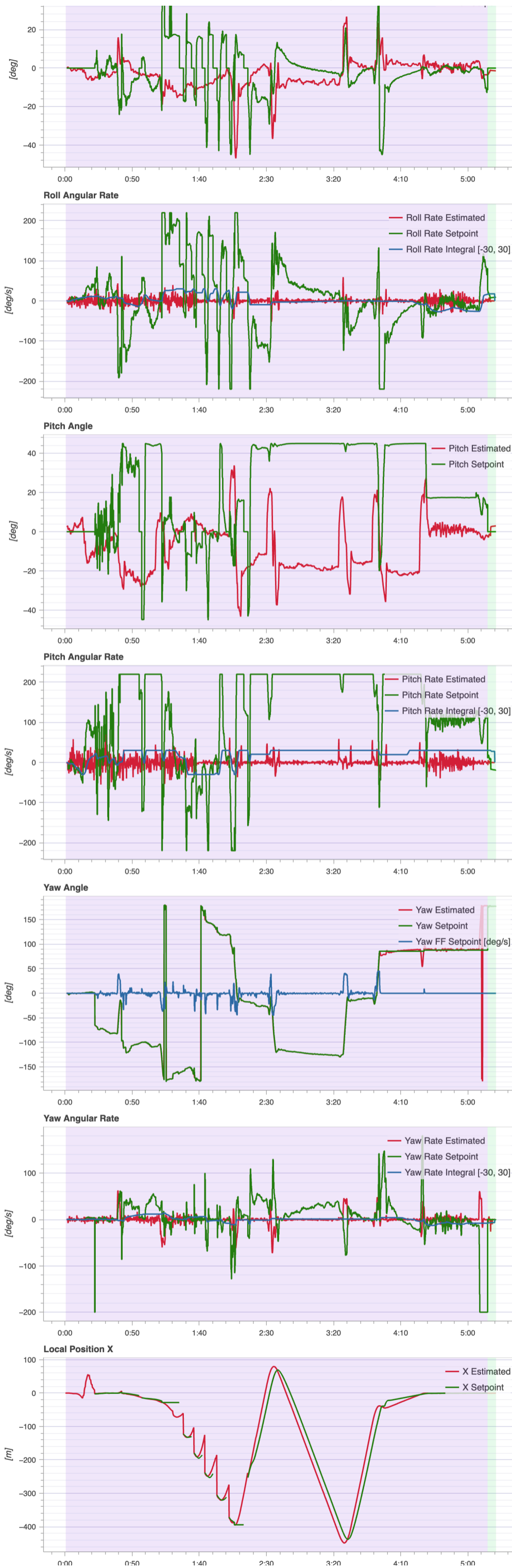
06_11_44_replayed.ulg

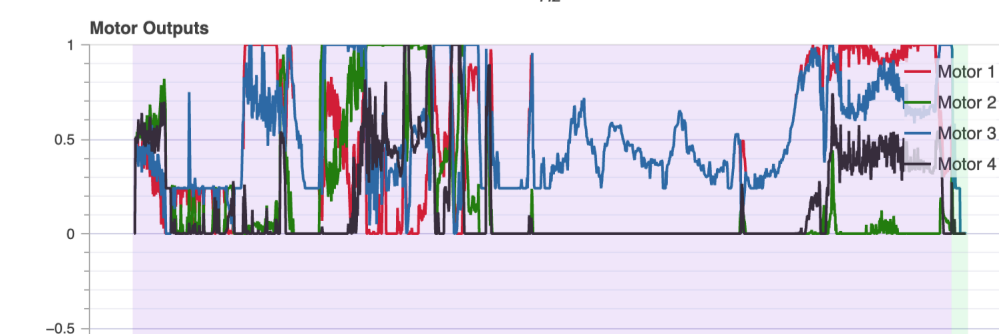
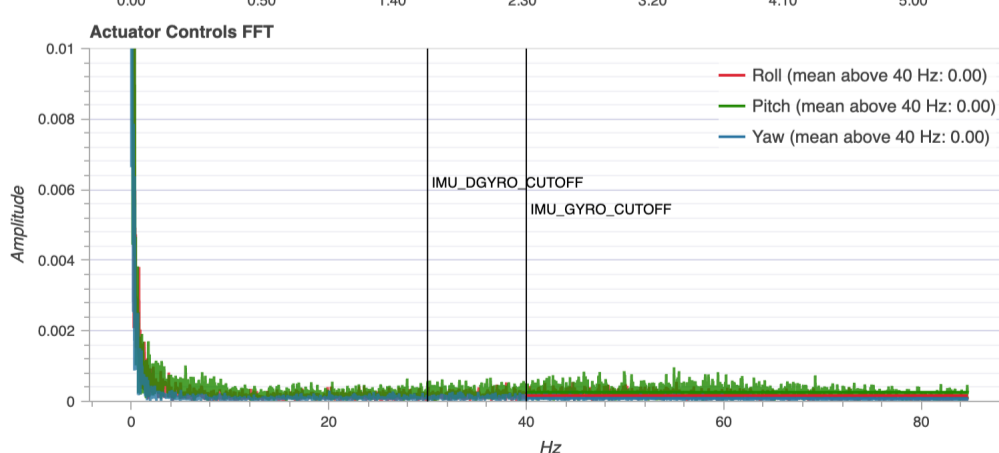
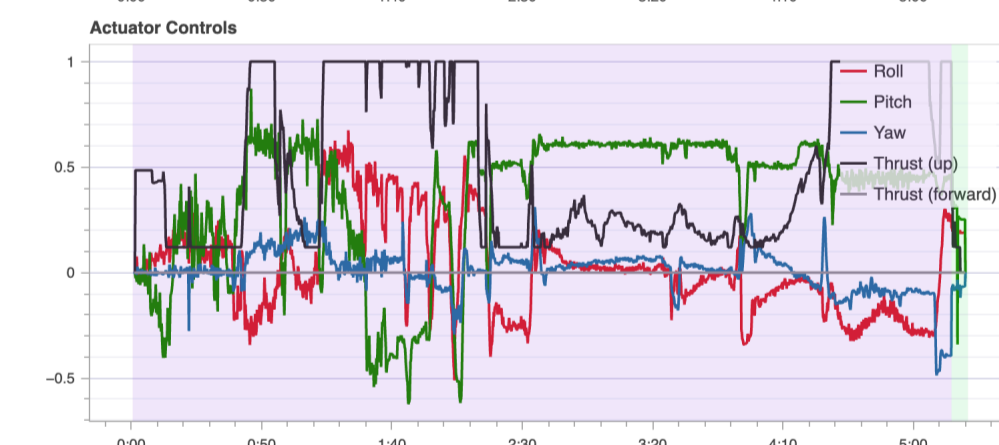
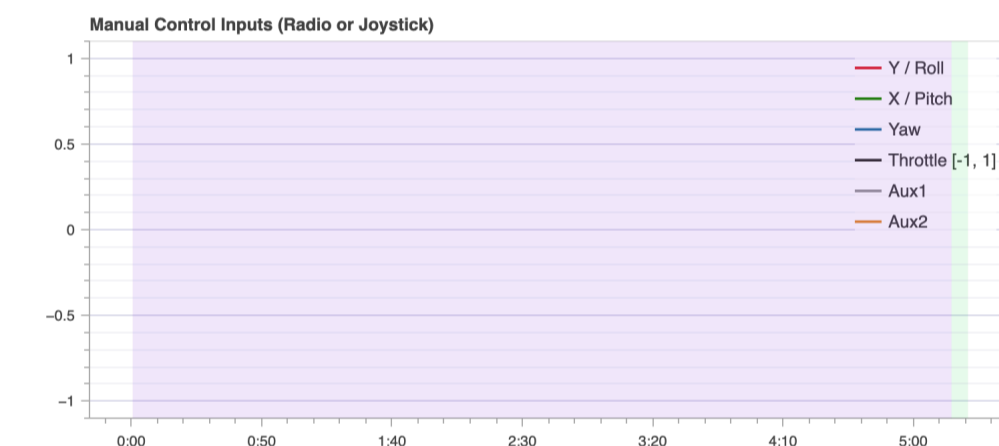
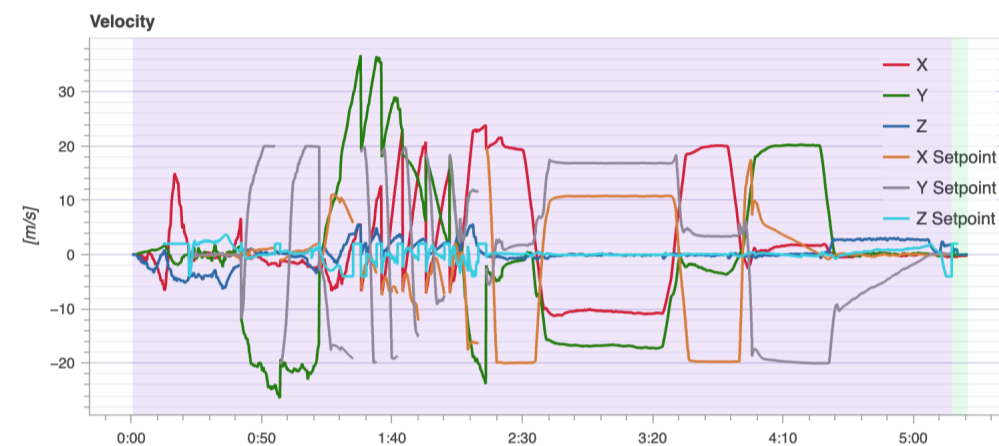
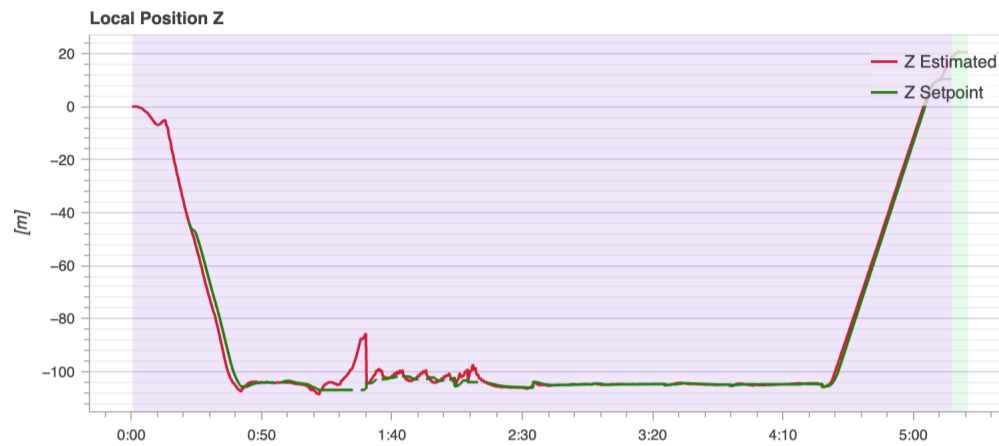
Airframe: 22422
 Hardware: PX4_SITL
 Software: [12352735](#)
 Version: branch: system_replay
 OS: Linux, v6.8.0
 Estimator: EKF2
 Logging Start: 28-03-2024 10:25
 Logging Duration: 0:05:20
 Vehicle Life Flight Time: 14 minutes 55 seconds

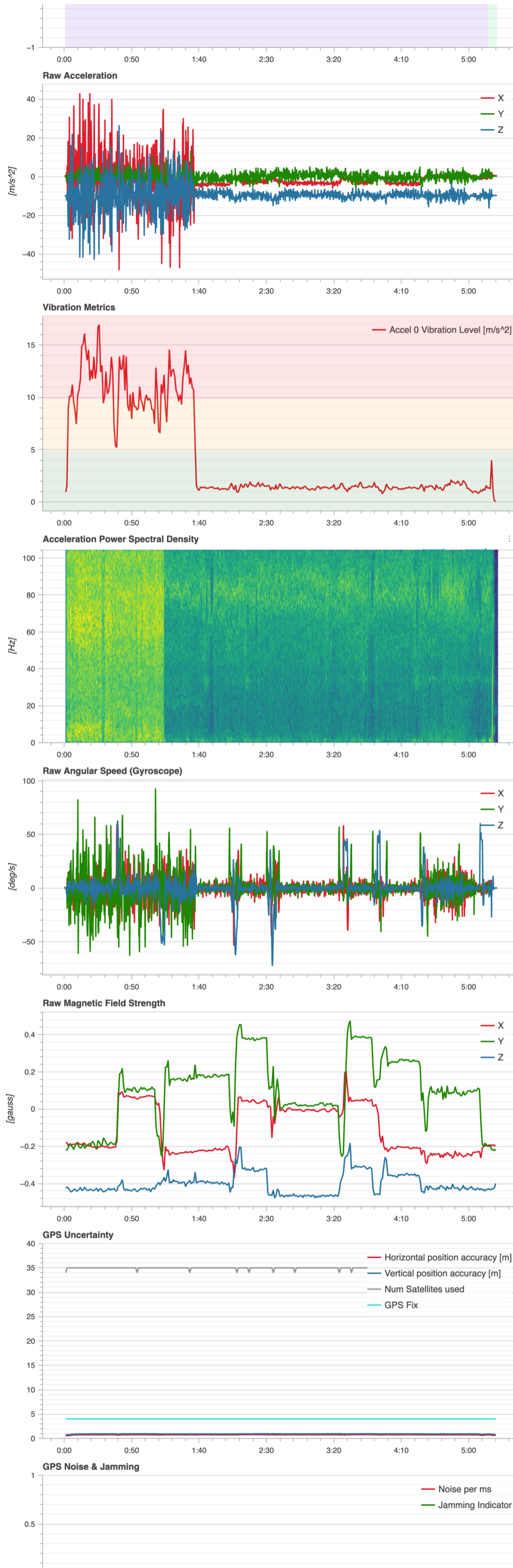
Feedback: Input topics:
 vehicle_command_ack,vehicle_command,vehicle_control_mode,vehicle_constraints,vehicle_status,battery_status>manual_control_setpoints,vehicle_air_data,vehicle_land_det

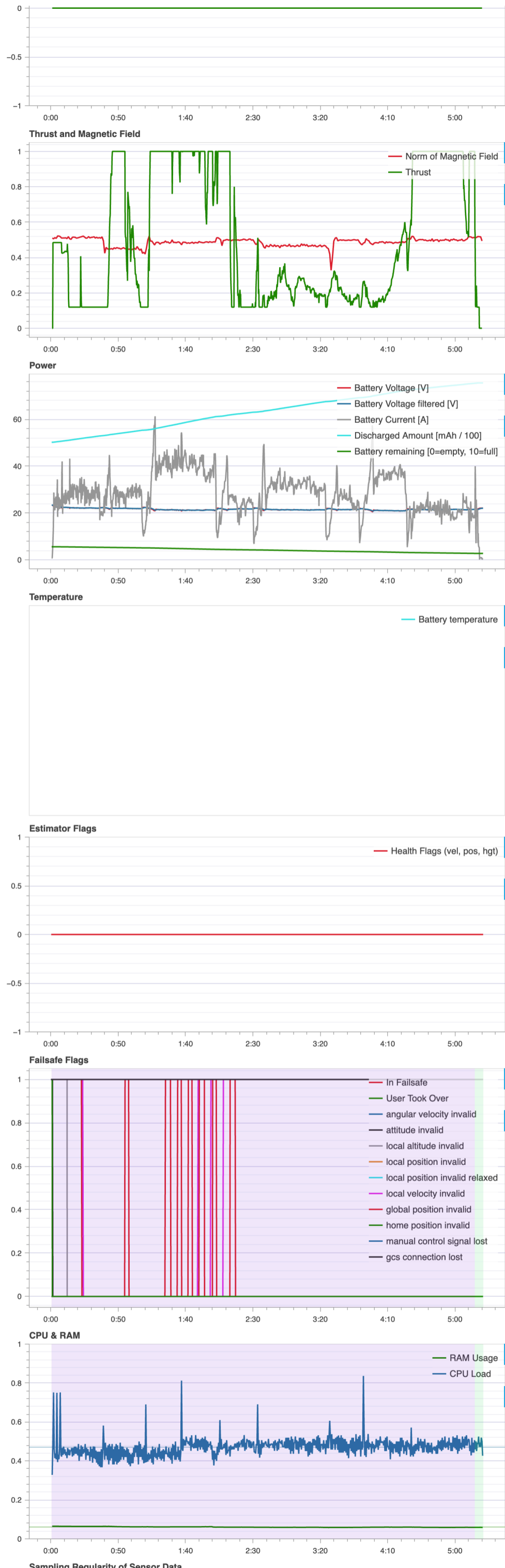
Add a detected error...

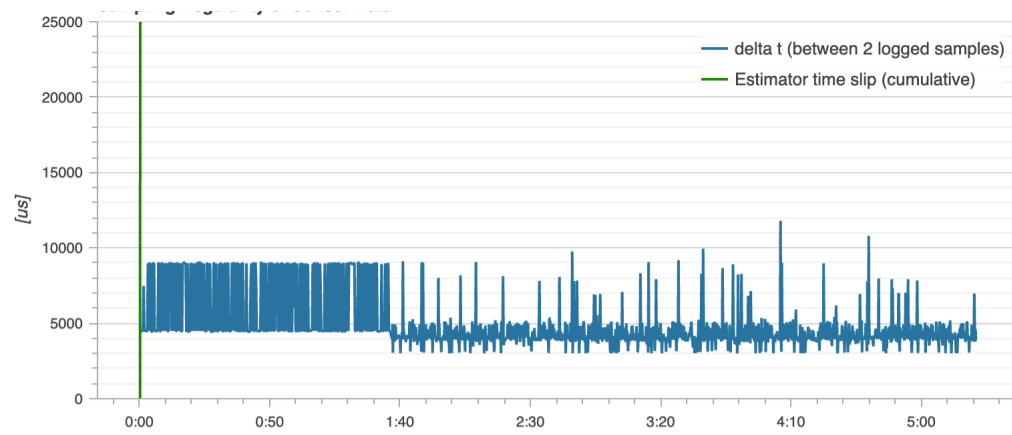











Non-default Parameters (except RC and sensor calibration)

#	Name	Value	Frame Default	Min	Max	Description
0	BAT1_CAPACITY	11500	-1			(unknown)
1	BAT1_N_CELLS	6	4			(unknown)
2	BAT1_R_INTERNAL	0.004999999888241...	0.004999999888			(unknown)
3	BAT1_SOURCE	0				(unknown)
4	BAT1_V_CHARGED	4.050000190734863	4.05000019073			(unknown)
5	BAT1_V_EMPTY	3.5999999046325684	3.59999990463			(unknown)
6	BAT1_V_LOAD_DROP	0.10000000149011612	0.10000000149			(unknown)
7	CA_AIRFRAME	0				(unknown)
8	CA_FAILURE_MODE	0				(unknown)
9	CA_METHOD	2	2			(unknown)

Logged Messages

#	Time	Level	Message
0	0:00:00	INFO	logging: opening log file 2024-5-2/6_11_44.ulog
1	0:00:00	INFO	[vehicle_angular_velocity] VehicleAngularVelocity UpdateSampleRate failed
2	0:00:00	INFO	[px4_work_queue] WorkQueue::Run: vehicle_magnetometer
3	0:00:00	INFO	[px4_work_queue] WorkQueue::Run: land_detector
4	0:00:00	INFO	[vehicle_angular_velocity] sample_rate_hz=0.000000, publish_rate_hz=0.000000
5	0:00:00	INFO	[ekf2] EKF2::Run() - sensor_combined_sub.update(&sensor_combined);
6	0:00:00	INFO	[uORB] not allowing replay to publish topic vehicle_thrust_setpoint
7	0:00:00	INFO	[uORB] orb_publish: estimator_aid_src_fake_hgt
8	0:00:00	INFO	[replay] HandlingTopicUpdate for estimator_local_position
9	0:00:00	INFO	[mc_pos_control] MulticopterPositionControl::Run()