

Solar Drone

ECE445 Final Report

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I. Introduction

A. Problem Description

Unmanned Aerial Vehicle (UAV), or commonly known as drone, is a type of aircraft without a human pilot on board, as the name suggested, but controlled autonomously by computers and/or taking commands from remote stations. The UAVs are perfect candidates for tasks that are tedious or dangerous for human, for example, patrolling along boarder lines, wild fire control, aerial surveillance and etc. The applications of UAV, as described above, generally require long flight time and reliable power supply. However, current UAV designs utilizing traditional battery or fuel cells usually struggles to meet such requirement.

B. Objectives

This project aims to provide an innovative solution to this problem by introducing the current popular photovoltaic system into the UAV power system design. It focuses on the electrical system design and the product will be a platform for future development on solar powered UAVs. The design is to be modular for easy module upgrade and replacement.

The UAV has a vast variety of configurations. The type of UAV chosen for this project is quadrotor helicopter, or called quadcopter, for its benefit as being easy to configure and having space for solar panel placement.

A prototype software flight controller will also be designed to be the interface between human and the electrical system.

C. System Block Diagram

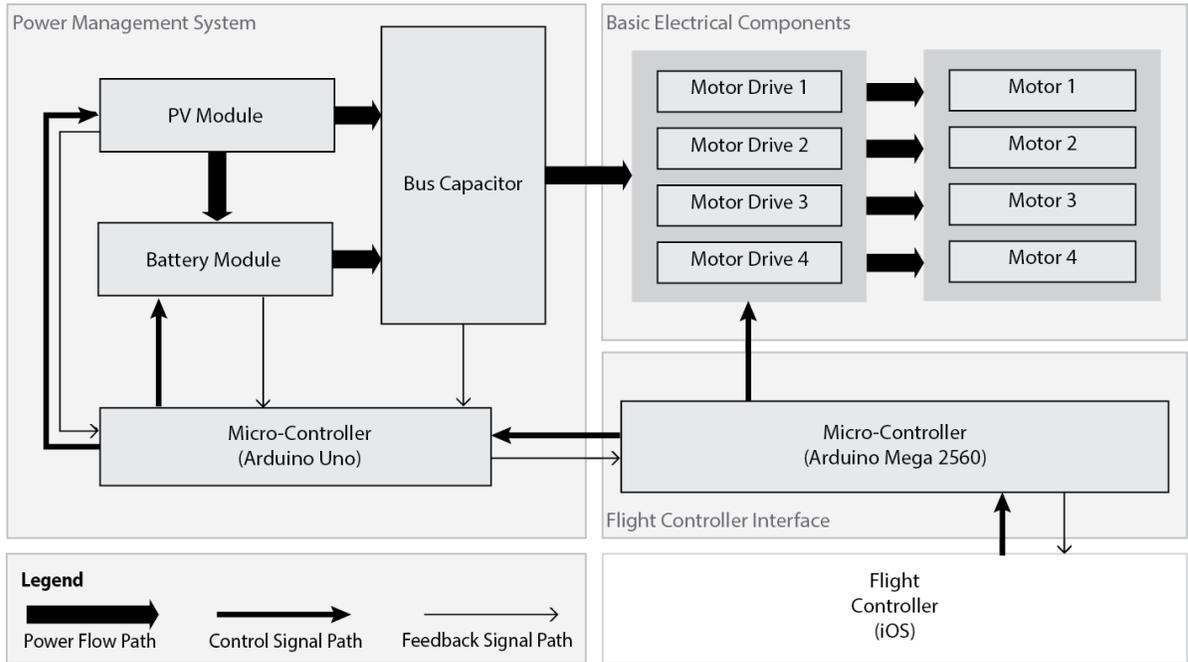


Figure 1 Top Level System Block Diagram

II. Design

A. Power Management System

1. Circuit Diagram

Since the input voltage from the solar module is between 6V to 11V and the required output voltage is 12V with variations less than 8%, a boost converter is proposed. For a boost converter, the relationship between the input and output voltage is as follows:

$$\frac{V_{out}}{V_{in}} = \frac{1}{1-D} \quad [1]$$

where D is the duty ratio of gate control signal to the MOSFET switch.

Circuit diagram is shown in Figure 2 below.

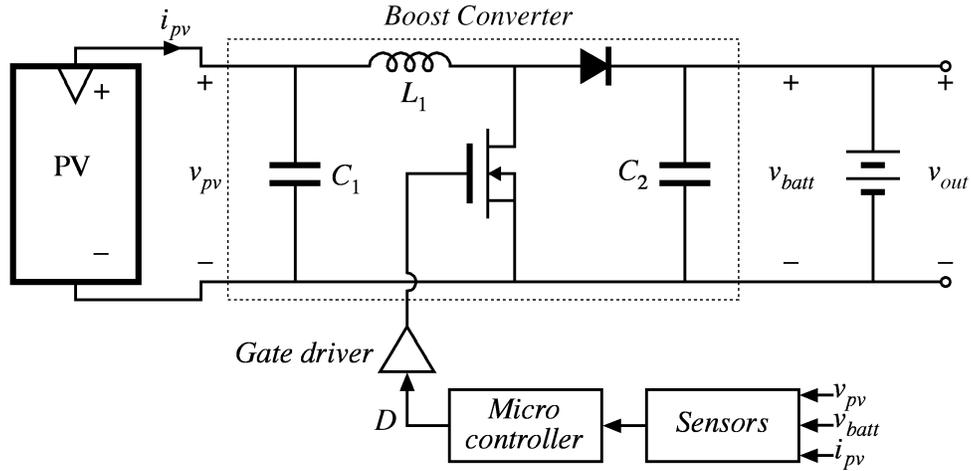


Figure 2 Power Management System Circuit Diagram

2. Components Selection

To ensure the proposed converter work in continuous conduction mode under all conditions, the inductance needs to be larger than the maximum value of critical inductance.

It can be determined as shown below:

$$L_{crit} = \frac{D \cdot V_{in}}{f_{sw} \cdot I_{ripple}} \quad [2]$$

Switching frequency is about 50kHz, and ripple current is set to 0.3A. $L_{critical}$ is maximized to be 120 μ H. In the circuit, 330 μ H inductor was used.

Since the peak-to-peak output voltage ripple should be 0.5V. Capacitance can be calculated as:

$$C \geq \frac{D \cdot I_{ripple}}{\Delta v \cdot f_{sw}} \quad [3]$$

The capacitor needs to be at least $1.5 \mu\text{F}$ to keep the voltage ripple within 0.5V . In this converter, the capacitor is chosen to be $470 \mu\text{F}$ to filter out additional high frequency noise.

As to the other components, the voltage and current requirements for them are 12 V and 20A .

Below is a table of other components used in the circuit and their ratings:

Table 1. MOSFET and Diode Rating

Components	Model	Voltage Rating (V)	Current Rating (A)
Diode	B40250TG	240	40
MOSFET	IRFPS3810	100	170

Apparently, components have ratings higher than required.

However, a basic boost converter itself cannot be used to function as a MPPT. Voltage sensors, current sensor, MOSFET driver and microcontroller should be added to the circuit. Sensors are used to sense voltage and current so that the microcontroller can calculate the power based on the values from the sensors.

Voltage divider circuit was used to function as a voltage sensor since the Arduino can only take up to 5V as input signal. Current sensor was built by using a current sensor chip.

3. Circuit Schematic

A fully functional MPPT circuit built in the project is shown in Figure 3, where the top yellow box shows input voltage sensor and red box shows the input current sensor.

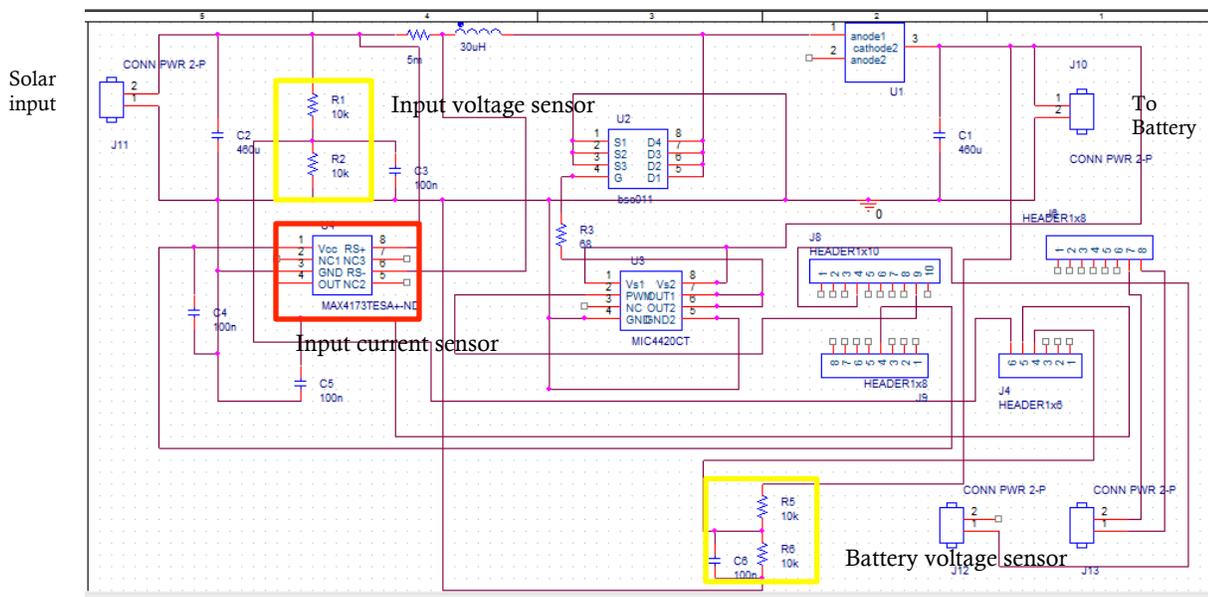


Figure 3 Power Management System Circuit Schematic

4. Control Algorithm

Since the output voltage is fixed by the battery, according to equation 1, input voltage can be swept by changing duty ratio which can be done by using the Arduino. [1] Based on the readings from the input sensors, powers input from solar panel can be calculated at different input voltages. The maximum power then can be found by doing the comparison between powers at different input voltages. I-V curve and P-V curve of a solar module are shown in Figure 4.

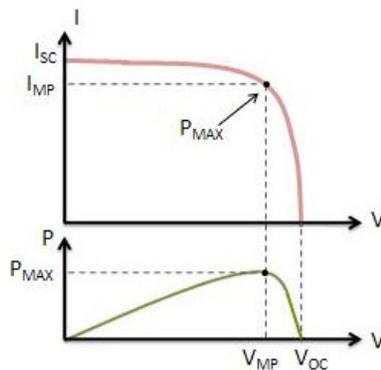


Figure 4 I-V and P-V curve of solar modules.

From the figure, it can be seen that the algorithm of the MPPT looks like climbing a hill. According to equation 1, if the input voltage is low, it will keep increasing by decreasing the duty ratio until the power hits its maximum value.

Sample codes are shown below:

```
If (old_power < power) {
    duty_ratio -= 1;
}
else duty_ratio += 1;
```

B. Electrical Components

1. Motor

A lightweight yet powerful DC motor is desired for this application. The motor needs to have low KV rating, thus higher torque capability, for heavy payload carrying. The specific motor chosen is Turnigy Aerodrive SK3 1185kv Brushless Outrunner Motor [2]. And the detailed specifications are tabulated in Table 2.

Table 2 Specifications for Turnigy Aerodrive SK3 1185kv Brushless DC Motor

Name	Value
RPM/V	1185kv
Internal resistance	0.024Ohm
Max Voltage	15V
Max Current	49A
Max Power	730W
Shaft Diameter	5.0mm
Weight	141g

2. Electronic Speed Controller (ESC)

The electronic speed controller functions as the motor drive and the speed is set by 50Hz 1ms to 2ms square wave signal, which could be obtained from Arduino. The ESC for this project is required to carry 15A, including ripple current, without overheating. The specific ESC chosen is Turnigy dLux 40A SBEC Brushless Speed

Controller. [3] This model has large heat sink for heat dissipation, high current rating and low battery protection function. The specifications for this ESC are tabulated in Table 3 below.

Table 3 Specifications for Turnigy dlux 40A SBEC Brushless Speed Controller

Name	Value
Max Cont. Current	1185kv
Max Burst Current	0.024Ohm
Max Voltage	24V
Size	45.5 x 33 x 23mm
Weight	54g

3. Battery

The battery is required to have high current capability and large capacity. The specific battery chosen for this project is Turnigy nano-tech 5000mah 65~130C Lipo Battery. [4] The battery contains three LiPo in series, each having 3.7V. And the battery can output maximum current of 325A.

C. Flight Controller and Interface

1. Overview

This prototype flight controller is built on iOS platform based on Objective-C language and is object-oriented. Four main objects are constructed till the date this report is written. They are Central Intelligent Unit, Motion Assistant, Communication Assistant and Arduino Assistant, as shown in Figure 5.

At the startup of the application, Central Intelligent Unit will be automatically allocated and initialized. Then it will allocate and initialize all the other three objects and connect them accordingly. All the objects operate independently while occasionally communicating with each other if necessary.

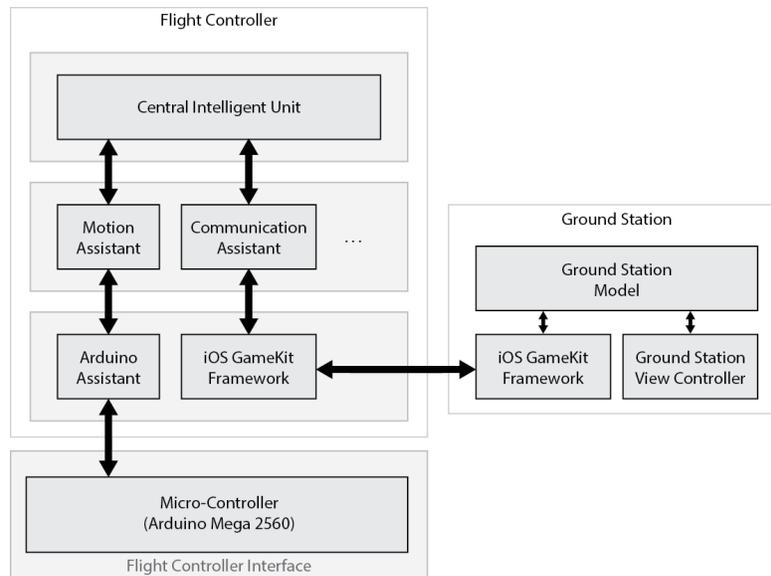


Figure 5 Flight Controller Block Diagram with Interface and Ground Station

2. Motion Update Loop

The information flow from Motion Assistant to Flight Controller Interface through Arduino Assistant creates the Motion Update Loop. This process is characterized by the flow chart depicted in Figure 6.

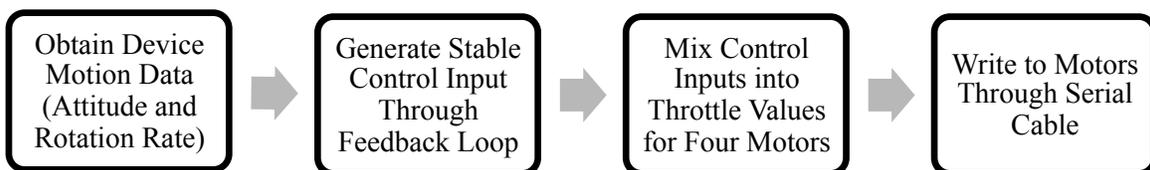


Figure 6 Motion Update Flow Chart

The feedback loop consists of one PI controller for attitude and one PID controller for rotation rate. [5] This feedback loop is experimental and is not part of this project. After the stable control inputs are generated, they will be mixed into four throttle values for four motors according to equation 4, assuming X-mode configuration.

$$\begin{aligned}
Motor_{front-left} &= \text{constrain}(throttle_{control} + \sin(45^\circ)pitch_{stable} + \sin(45^\circ)roll_{stable} - yaw_{stable}, throttle_{max}, throttle_{min}) \\
Motor_{front-right} &= \text{constrain}(throttle_{control} + \sin(45^\circ)pitch_{stable} - \sin(45^\circ)roll_{stable} + yaw_{stable}, throttle_{max}, throttle_{min}) \quad [4] \\
Motor_{back-left} &= \text{constrain}(throttle_{control} - \sin(45^\circ)pitch_{stable} + \sin(45^\circ)roll_{stable} + yaw_{stable}, throttle_{max}, throttle_{min}) \\
Motor_{back-right} &= \text{constrain}(throttle_{control} - \sin(45^\circ)pitch_{stable} - \sin(45^\circ)roll_{stable} - yaw_{stable}, throttle_{max}, throttle_{min})
\end{aligned}$$

Finally, the motor throttle values will be packed using the predefined protocol, as shown in Table 4, and sent to Arduino.

Table 4 Protocol for Transmitting Motor Throttle Packets

7	6	5	4	3	2	1	0	
CMD/DATA	CMD INFO				CMD2	CMD1	CMD0	INFO
1	-	-	-	0	0	0	0	DATA LOST
1	CMD 2:0				1	0	0	PACKET CORRUPTED
1	MOTOR-A 8:7		MOTOR-B 8:7		0	0	1	MOTOR DATA
0	MOTOR-C 8:7		MOTOR-D 8:7		-	-	-	
0	MOTOR-A 6:0							
0	MOTOR-B 6:0							
0	MOTOR-C 6:0							
0	MOTOR-D 6:0							

3. Communication With Ground Station

The communication with ground station is based on iOS GameKit framework and utilizes Bluetooth for transmitting packets. This function is easily achieved through implementing encoding and decoding protocols required by GameKit framework. For detailed explanation on GameKit framework, refer to reference [6].

III. Requirements and Verifications

A. Power Management System

1. Requirements

- (1) The system bus voltage should be constant at 12V, with variations less than $\pm 5\%$.
- (2) It should enable charging to the battery when there is power surplus in the system and stop charging when the battery is full.
- (3) PV modules output maximum power possible at any time.

2. Test Cases and Procedures

20W, which is under the irradiance of $1000\text{W}/\text{m}^2$, PV module was connected to the MPPT circuit input connectors. Output connectors of the MPPT circuit were connected to a constant current of 2A electronic load. Additionally, a DC power supply with 12 V simulating the battery was connected to the electronic load. A 1200W lamp was used to simulate sunlight. The PV module, which was borrowed from power lab, tested on was labeled to have a maximum power voltage of 9.5V

3. Results

The data recorded by Arduino are tabulated in Table 5 and shown below

Table 5 Maximum Power Point Tracking Test Results

Time (s)	D (%)	V _{pv} (V)	I _{pv} (A)	P _{out} (W)	V _{out} (V)
0	100	0.29	0	0	11.88
5	96	5.19	0.53	2.75	11.84
10	90	5.34	1	5.34	11.84
15	84	5.36	1.02	5.47	11.88
20	69	5.54	1.02	5.65	11.88
25	47	6.94	1	6.94	11.91
30	32	8.47	0.87	7.37	11.95
35	20	9.76	0.77	7.52	11.95
40	19	9.89	0.75	7.42	11.91
45	20	9.76	0.77	7.52	12.06

4. Discussion

As it can be seen from the table above, power output from the solar module kept increasing as duty ratio decreased until it hit 7.5W. Then the duty ratio stabilized around 20%. This confirmed the fact that our circuit was able to find the maximum power. Furthermore, the input voltage stabilized at 9.8V which is very close to the labeled value, which is 9.5V. This is also an evidence to prove that our MPPT circuit was able to find the maximum power of the solar module.

The reason for not getting rated power at 20W may come from the non-ideal light source. The reason may be the fact that the lamp was consuming 1.2 kW of input power but was producing much less power in the form of visible light than that since an incandescent light bulb is not very efficient. Thus, it would not be surprising to find that the power output was much lower.

B. Electrical Components

1. Requirements

(1) The battery should be able to provide 600W power output when the PV module is completely offline.

(2) Four motors when paired with 15inches propeller with 4inches pitch should be able to provide more than 2kg of thrust with less than 600W of power consumption.

(3) Each ESC should be able to handle 15A of continuous current without failing when the power system is operating at max power condition (600W).

2. Test Procedures

Step 1: Install each motor on testing bracket, which is placed on weigh scales respectively.

Step 2: Setup the ESC according to user manual so that the propeller would generate a force downward, pushing the weight scale.

Step 3: Load Servo testing program onto Arduino Mega, which allows user to control the throttle output via computer.

Step 4: Connect the battery to power distribution board through a watt meter, which then connects to the four ESCs through watt meters measuring individual current flowing in each channel.

Step 5: Connect JR connectors on ESCs to pin2, pin5, pin12 and pin13 on Arduino board.

Step 6: Record readings from weigh scale and wattmeter.

3. Results

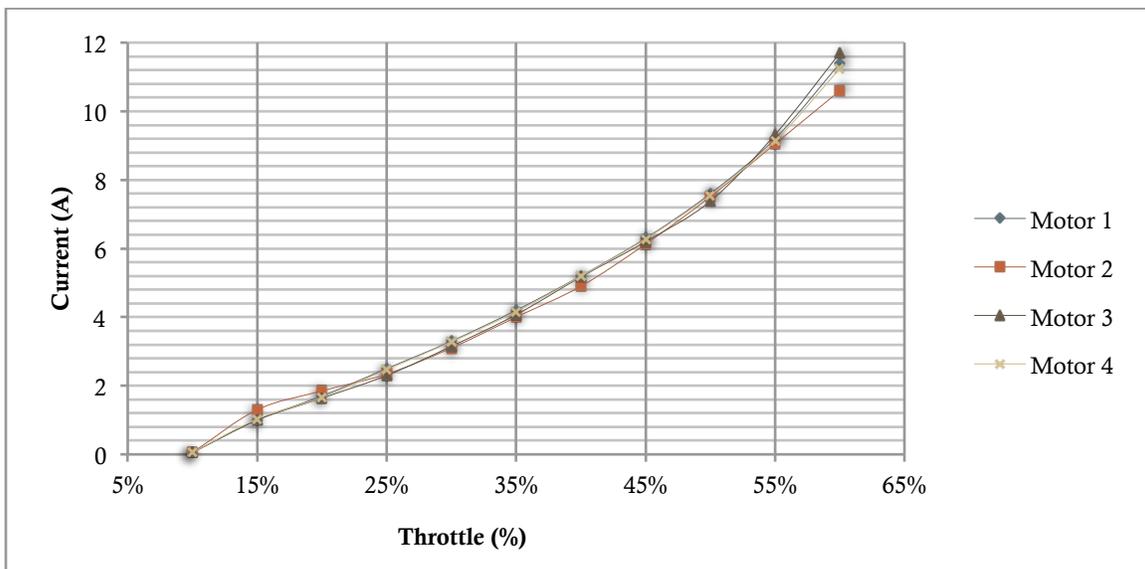


Figure 7 Current vs Throttle

Figure 7 shows the current flowing into the ESC at 10% to 60% throttle. 4 motors behave almost the same with minor variations. Maximum current motor draws at 60% throttle is 11.7A

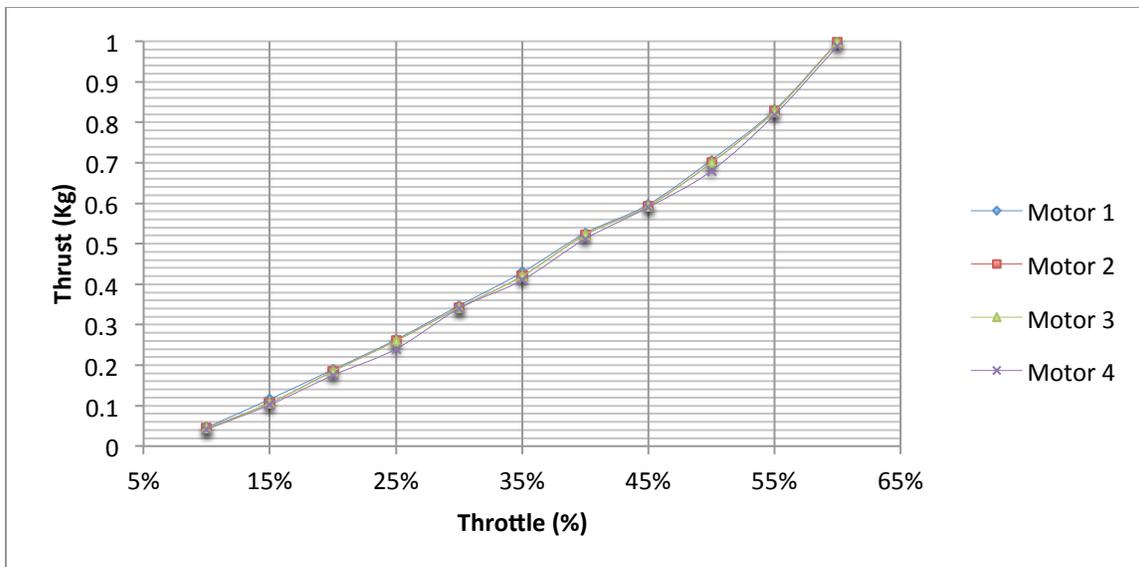


Figure 8 Thrust vs Throttle

This figure shows the thrust each motor can generate from 10% to 60% throttle. 4 motors behave almost the same. Thrust each motor can generate at 60% throttle is approximately 1kg, which is equal to 10N.

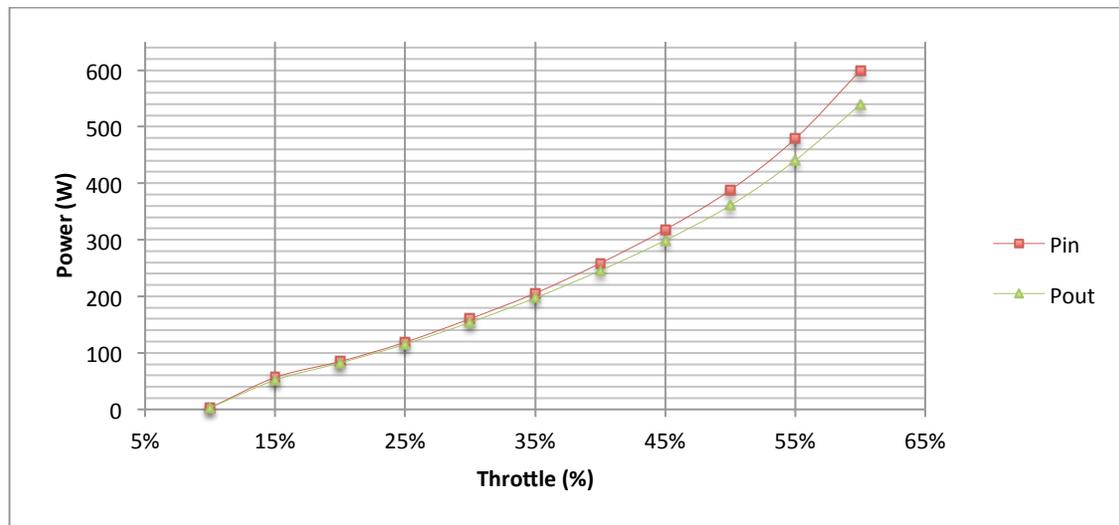


Figure 9 Power from battery vs power consume by motor

This Figure shows power coming out from battery collected from reading of wattmeter and power consumed by four motors using $P=VI$.

4. Discussion

The ESC has a continuous current rating at 40A so that 12A of current is safe for the ESC to handle. The quadcopter has an approximate weight of 2kg, so that 1 kg thrust at 60% throttle per motor is capable of lifting up the quadcopter. The efficiency of power flowing in and power consumed is approximately 90% when throttle is at 60%. With these verifications, ESC, motor and battery are able to provide enough thrust and the quadcopter can hover for 15 minutes only with battery power supply.

C. Flight Controller and Interface

1. Test Procedures and Results

a. Measure Loop Time on iOS Side

Step 1: Connect iPhone 4 to a computer running Mac OSX 10.8.0 or above, with Xcode 4.5.1 or above.

Step 2: In define.h, add `#define mode profiling`. Compile and run SolarDrone project on the connected iPhone 4

Step 3: The loop time will be displayed on iPhone 4 and time is averaged to be 1.1ms

b. Measure Loop Time from iOS to Arduino

The time it takes to transfer data from iOS to Arduino is hard to measure due to large lag time for acknowledgement packet transferred from Arduino back to iOS.

But this lag could be negligible if acknowledging every 100 packets transferred.

Step 1: Add `#define mode profiling` to Arduino Program. Compile and run on Arduino Mega 2560.

Step 2: Similar to part a above, compile and run SolarDrone project on iPhone 4, all the acknowledgement packet sent from Arduino will be logged in log console with accurate time stamp.

Step 3: Take neighboring two logs, calculate the time difference and divided by 100, the result will be transfer time plus 10ms loop interval. And the final result is averaged to be 0.3ms.

2. Discussion

The results from both part a and part b add up to 1.4 ms, which is far less than 10ms individual loop time. This guarantees that the loop will be completed on time before the next invocation. This proves the iPhone 4 is capable to stabilize the quadcopter and be the flight controller.

IV. Costs

A. Parts

Item	Quantity	Unit Price (US\$)	Total Price(US\$)
Turnigy Talon Carbon Fiber Quadcopter Frame	1	28.78	28.78
Brushless Speed Controller Programming Card	1	3.32	3.32
Slow Fly Electric Prop 12x4.5R SF (4 pc Right Hand Rotation)	1	4.26	4.26
Hobby King Quadcopter Power Distribution Board	1	3.99	3.99
Male XT60 connectors (5pcs/bag) GENUINE	1	2.44	2.44
Female XT60 connectors (5pcs/bag) GENUINE	1	2.35	2.35
Turnigy nano-tech 5000mah 65~130C Lipo Battery	1	33.7	33.7
Adruino MEGA 2560 Board	1	49.99	49.99
Arduino UNO	2	21	42
19% 4.5w 6" 156mm*156mm Mono solar cell	45	3.79	170.55
Propeller	4	24.62	98.48
iPhone 4	1	499	499
AttoPilot Voltage and Current Sense Breakout - 90A	1	19.95	19.95
TMP36 - Temperature Sensor	10	1.35	13.5

Ultrasonic Module HC-SR04 Distance Sensor For Arduino	1	6.8	6.8
MBRB4030-D	4	2.94	11.76
Turnigy Aerodrive SK3 - 3542-1185kv	4	31.27	125.08
Turnigy dlux 40A SBEC Brushless Speed Controller	4	20.29	81.16
Capacitor: 470 uH	2	0.62	1.24
Resistor: 4.1k Ω	1	0.07	0.07
Resistor: 1.5k Ω	1	0.07	0.07
Capacitor: 0.1uH	4	0.83	3.32
Connector: WM7853-ND	2	2	4
Inductor: 330uH 2100LL-331-H-RC	1	2.63	2.63
Resistor: 5m Ω 12FR005E-ND	3	5.19	15.57
Resistor: 10k Ω 10KQBK-ND	2	0.14	0.28
Heat Sink HS106-ND	3	1.35	4.05
MOSFET: IRFPS3810	1	11.94	11.94
DIODE: B40250TG	1	2.02	2.02
MOSFET Driver: MIC 4420CT	1	2.94	2.94
Current Sensor: MAX4173H	1	2.81	2.81
Total Cost			1248.05

B. Labor

Name	Salary(\$/hr)	Hours	Total	Total * 2.5
Jie Wang	40	180	7200	18,000
Jinming Zhang	40	180	7200	18,000
Yingkan Ni	40	180	7200	18,000
Total			\$54,000	

Labor (US\$)	Parts(US\$)	Grand Total(US\$)
54,000	1248.05	55,248.05

V. Conclusion

A. Accomplishment

A working power management system is designed, fabricated and tested in this project. Such power management system is able to prolong the flight time of quadcopter, as opposed to that with only battery on board. The electrical system is

also designed and assembled for functionality testing. Besides, a prototype software flight controller is designed for future development.

B. Difficulties and Uncertainties

(1) Mounting solar panels onto the quadcopter is hard to achieve since solar panels are fragile and vulnerable, it is easy to cause damage to the solar panels.

(2) Currently, the best solar cells available in the market possess an efficiency of approximately 20%, which is only able to prolong the flight time.

(3) The PID system embedded in the quadcopter is hard to tune due to lack of modeling information for the .

C. Ethical Considerations

We abide to the IEEE code of Ethics in designing and testing the system as follows:

1. to accept responsibility in making decisions consistent with the safety, health, and welfare of the public, and to disclose promptly factors that might endanger the public or the environment;
3. to be honest and realistic in stating claims or estimates based on available data.
7. to seek, accept, and offer honest criticism of technical work, to acknowledge and correct errors, and to credit properly the contributions of others
9. to avoid injuring others, their property, reputation, or employment by false or malicious action.

Since each motor is able to spin at 11850 rpm at full throttle, it turns out to be very dangerous incase it lost control. So we start with using three motors to test the self-

balancing system and hangs the quadcopter to a rod to make sure it would not fly all around and cause damage.

D. Future Work

We have achieved most of goals we set at the beginning of the semester. There are still some issues regarding stability of the quadcopter. We need to set up a model for this system to model the behavior of in-flight characteristics of the quadcopter so that we will be able to find the right pole locations for the PID system.

Since we used iOS as our developing language, we are able to build a platform for other developers to join us, who can contribute more features.

VI. References

- [1] Buckley, Bryan. "mppt: a maximum power point tracking photovoltaic system."
<<http://bama.ua.edu/~bwbuckley/projects/mppt.html>>
- [2] Hobbyking "Turnigy Aerodrive SK3 - 3542-1185kv Brushless Outrunner Motor"
<http://www.hobbyking.com/hobbyking/store/uh_viewItem.asp?idProduct=30851 >
- [3] Hobbyking "Turnigy dlux 40A SBEC Brushless Speed Controller"
<http://www.hobbyking.com/hobbyking/store/uh_viewItem.asp?idProduct=18922>
- [4] Hobbyking "Turnigy nano-tech 5000mah 3S 65~130C Lipo Pack"
<http://www.hobbyking.com/hobbyking/store/uh_viewItem.asp?idProduct=19153>
- [5] ArduCopter <<http://code.google.com/p/arducopter/>>
- [6] Apple Documentations for GameKit
<http://developer.apple.com/library/ios/#documentation/GameKit/Reference/GameKit_Collection/_index.html >

VII. Appendix

Servo Testing Program

```

void setup(){
  Serial.begin(57600);

  pinMode(2, OUTPUT);
  pinMode(5, OUTPUT);
  pinMode(11, OUTPUT);
  pinMode(12, OUTPUT);

  initPWMs();
  i = 0;
  //Serial2.flush();
  Serial.println("..Type \"v\" and number between
2000 to 4000, e.g. v2500");

  delay(500);
  //sensor
}

void loop (){
  //sensor
  // float temprature0 = (analogRead(sensorPin) *5
/1024.0-0.5)*100.0;
  // if(temprature!=temprature0){
  //   Serial.println(temprature0);
  //   temprature=temprature0;
  // }

  if (Serial.available() >0) {

    buffer[i++] = Serial.read();
    if (buffer[0] != 'v'){
      i = 0;
    }
    if (i>4){
      char cmd[4];
      cmd[0] = buffer[1];
      cmd[1] = buffer[2];
      cmd[2] = buffer[3];
      cmd[3] = buffer[4];
      int value = atoi(cmd);
      OCR1A = value;
      OCR1B = value;
      OCR3A = value;
      OCR3B = value;
      Serial.println(String(value));
      i = 0;
    }
  }
}

void initPWMs(){
  TCCR1A
=((1<<COM1A1)|(1<<COM1B1)|(1<<WGM11)
); //Please read page 131 of DataSheet, we are

```

```

changing the registers settings of
WGM11,COM1B1,COM1A1 to 1 thats all...
  TCCR1B =
(1<<WGM13)|(1<<WGM12)|(1<<CS11);
//Prescaler set to 8, that give us a resolution of
0.5us, read page 134 of data sheet
  OCR1A = 0x0000; // Init ODR registers to nil
output signal
  OCR1B = 0x0000;
  ICR1 = 40000; //50hz freq...Datasheet says
(system_freq/prescaler)/target frequency. So
(16000000hz/8)/50hz=40000
  TCCR3A
=((1<<COM1A1)|(1<<COM1B1)|(1<<WGM11)
);
  TCCR3B =
(1<<WGM13)|(1<<WGM12)|(1<<CS11);
  OCR3A = 0x0000;
  OCR3B = 0x0000;
  ICR3 = 40000;
}

```

```

Flight Controller Interface
#define Serial0 Serial
#define isCommand(onebyte) (0x80&onebyte==0)
? false:true

```

```

int byteCount = 0;
char rxBuffer[128];
int rxIndex = 0;
uint32_t motor[4];

```

```

void setup(){
  Serial2.begin(57600);
  Serial1.begin(9600);
  Serial0.begin(115200);
  pinMode(2, OUTPUT);
  pinMode(5, OUTPUT);
  pinMode(11, OUTPUT);
  pinMode(12, OUTPUT);

  initPWMs();
  //Serial2.flush();
  Serial0.println("Initialization Done.");

```

```

  delay(500);
}

```

```

void loop (){
  if (Serial1.available() >0){
    Serial1.flush();
    Serial2.write("a");
  }
  if (Serial2.available() >0) {
    uint8_t firstByte = Serial2.peek();
    if(0x80&firstByte){

```

```

uint8_t cmd = firstByte & 0x7;
switch(cmd){
  case 0:
    break;

  case 1:
    if (Serial2.available() >=6 ) {
      uint8_t packet[6];
      Serial2.readBytes((char*)packet,6);
      //sanity check?
      motor[0] = ((uint32_t)((packet[0]&0x60)<<2 |
packet[2]))*125/32+2000;//*2000/512
      motor[1] = ((uint32_t)((packet[0]&0x18)<<4 |
packet[3]))*125/32+2000;//might use look up table
to trade memory for speed (2kb)
      motor[2] = ((uint32_t)((packet[1]&0x60)<<2 |
packet[4]))*125/32+2000;
      motor[3] = ((uint32_t)((packet[1]&0x18)<<4 |
packet[5]))*125/32+2000;
      OCR1A = motor[0];
      OCR1B = motor[1];
      OCR3A = motor[2];
      OCR3B = motor[3];
      //Serial0.println("CMD
1:"+String(motor[0])+" "+String(motor[1])+"
"+String(motor[2])+" "+String(motor[3]));
      byteCount += 6;
    }
    break;
}
// if(byteCount >= 1000){
//   byteCount = 0;
//   Serial2.write(18);
// }
}
else{
  //byte lost somewhere?
  //Serial0.println("---Detected Lost Byte---");
  Serial2.read();
}
}
if(Serial2.available())>=128){
  //Serial0.println("---Challenge---");
}
}

void initPWMs(){
  TCCR1A
=((1<<COM1A1)|(1<<COM1B1)|(1<<WGM11)
); //Please read page 131 of DataSheet, we are
changing the registers settings of
WGM11,COM1B1,COM1A1 to 1 thats all...
  TCCR1B =
(1<<WGM13)|(1<<WGM12)|(1<<CS11);
//Prescaler set to 8, that give us a resolution of
0.5us, read page 134 of data sheet
  OCR1A = 0x0000; // Init ODR registers to nil
output signal
  OCR1B = 0x0000;
  ICR1 = 40000; //50hz freq...Datasheet says
(system_freq/prescaler)/target frequency. So
(16000000hz/8)/50hz=40000
  TCCR3A
=((1<<COM1A1)|(1<<COM1B1)|(1<<WGM11)
);
  TCCR3B =
(1<<WGM13)|(1<<WGM12)|(1<<CS11);
  OCR3A = 0x0000;
  OCR3B = 0x0000;
  ICR3 = 40000;
}

```