The goal of this project is to create an open-source universal software framework to communicate with multiple Micro Aerial Vehicles (MAV). From the programmer's view, the communication interface is common to all supported MAV models, so the learning period is shortened and the modularity is increased by isolating the control software from the MAV technical specifics. Thanks to a proxy-based distributed architecture, MAVs without network capabilities can be integrated in the system and different networked configurations are made possible. Some application examples that are easily implemented with the proposed architecture are: heterogeneous MAV swarms, distributed processing of feedback signals, MAV sharing among researchers, onboard or off-board processing and control.


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