MANUAL*

* multirotors: attitude stabilized,
  fixed wing: mixing of manual inputs

MODE SW

ASSIST → POSCTL SW → ALTCTL / POSCTL

AUTO → RETURN SW → LOITER SW → MISSION / LOITER / RETURN

increasing autonomy

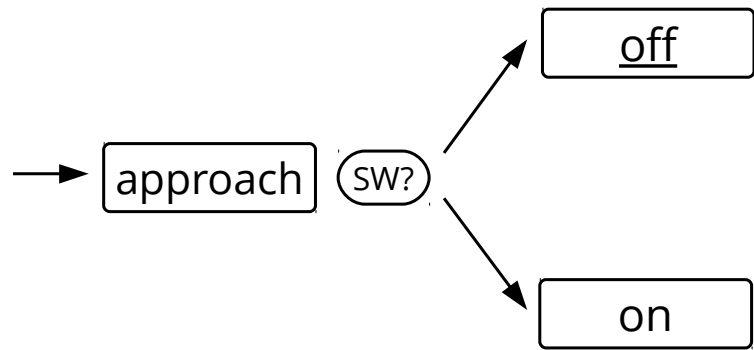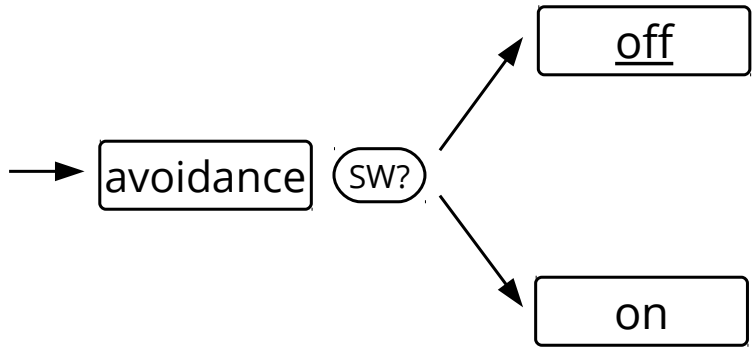MODE SW — Main mode switch (mandatory, 3 position)
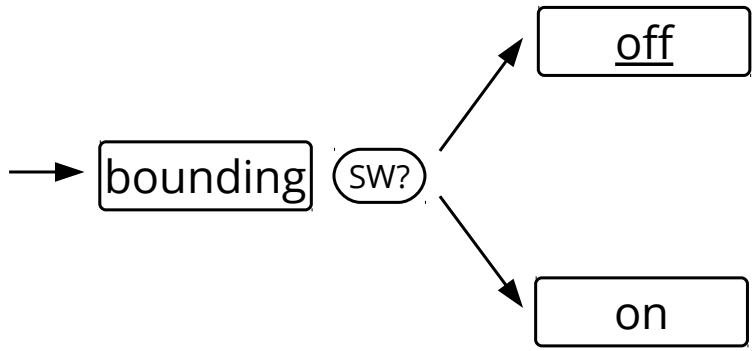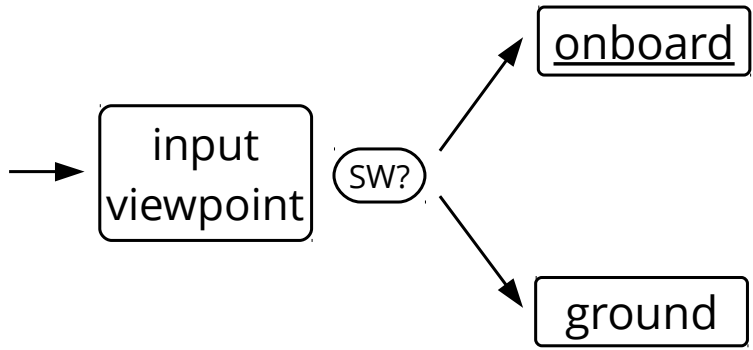
POSCTL SW — Position control switch (optional, 2 position, default value if not present)
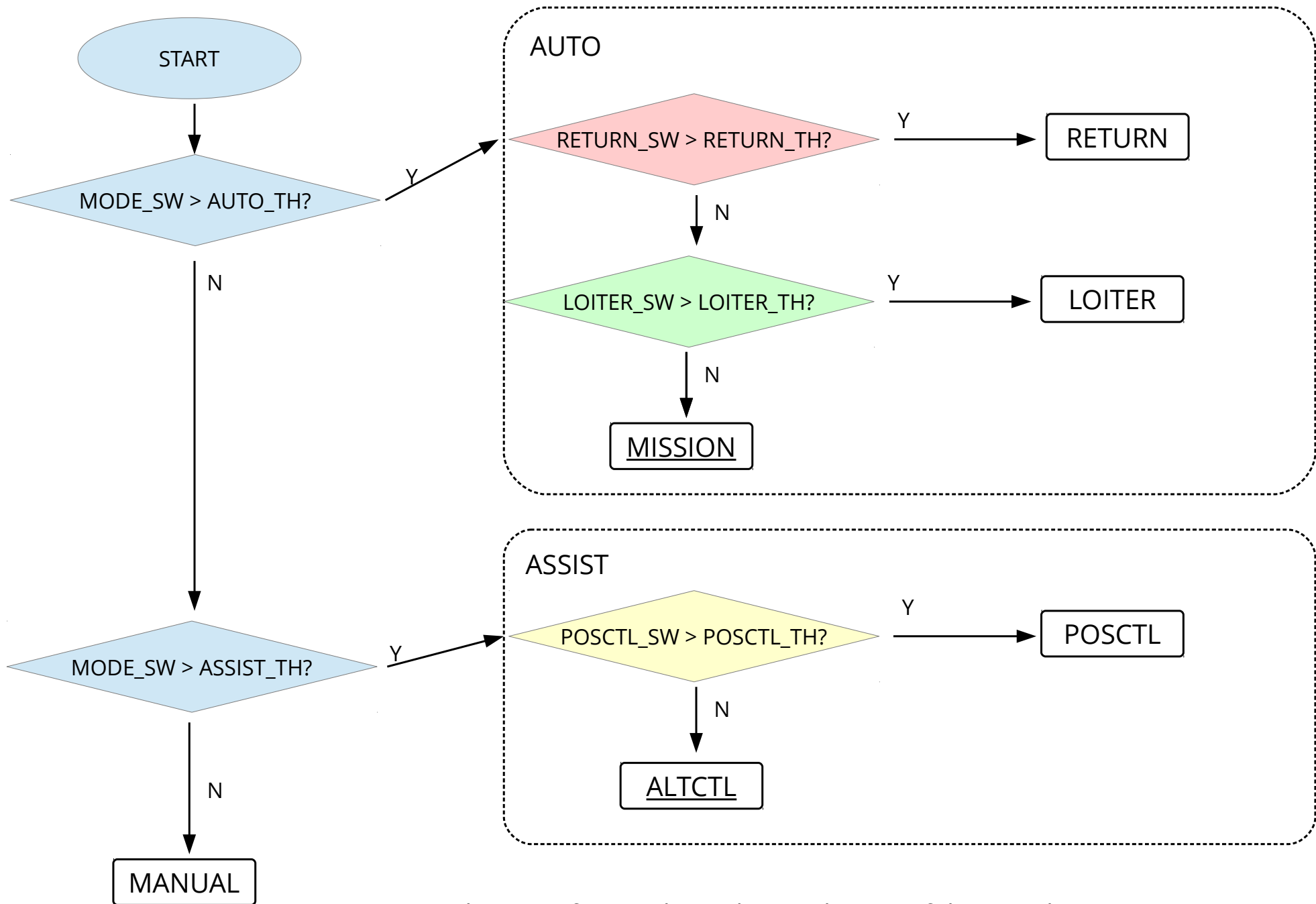
RETURN SW — Return switch (optional, 2 position, default value if not present)

LOITER SW — Loiter (pause mission) switch (optional, 2 position, default value if not present)

input viewpoint (SW?) → onboard / ground

bounding (SW?) → off / on

avoidance (SW?) → off / on

approach (SW?) → off / on

```
START

MODE_SW > AUTO_TH?
    │ Y
    └──────────► AUTO
                 ┌─────────────────────────────────────┐
                 │  RETURN_SW > RETURN_TH?  ──Y──► RETURN │
                 │         │ N                            │
                 │  LOITER_SW > LOITER_TH?  ──Y──► LOITER │
                 │         │ N                            │
                 │      MISSION                           │
                 └─────────────────────────────────────┘
    │ N

MODE_SW > ASSIST_TH?
    │ Y
    └──────────► ASSIST
                 ┌─────────────────────────────────────┐
                 │  POSCTL_SW > POSCTL_TH?  ──Y──► POSCTL │
                 │         │ N                            │
                 │      ALTCTL                            │
                 └─────────────────────────────────────┘
    │ N

MANUAL
```

AUTO

RETURN_SW > RETURN_TH?   Y → RETURN
                N
LOITER_SW > LOITER_TH?   Y → LOITER
                N
MISSION

ASSIST

POSCTL_SW > POSCTL_TH?   Y → POSCTL
                N
ALTCTL

MODE_SW > AUTO_TH?   Y
N

MODE_SW > ASSIST_TH?   Y
N

MANUAL

Note: Absence of a switch results in selection of the N path.