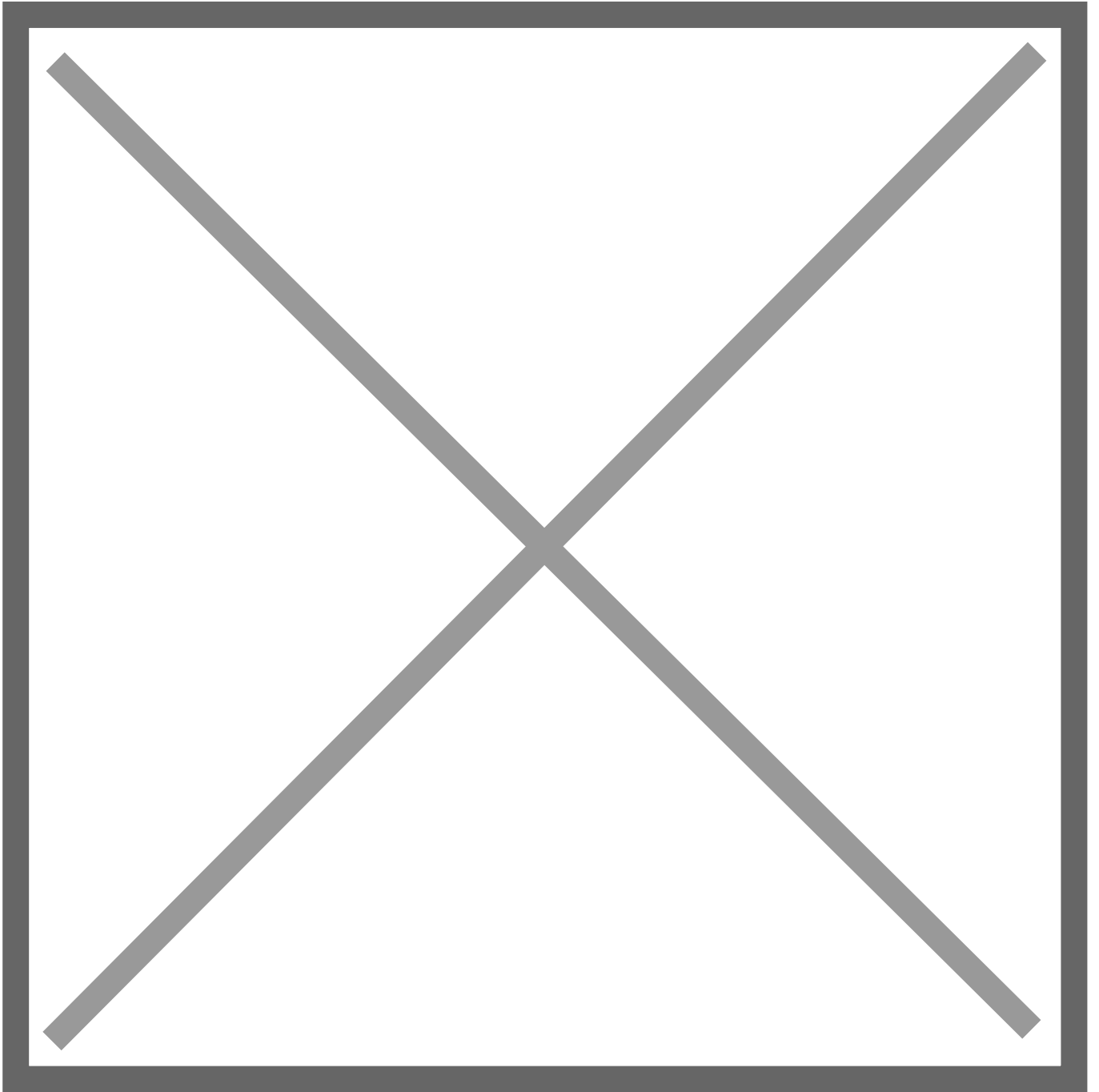


# Understanding the Project and the Blocks Used

This project includes several interconnected blocks. Below are the main blocks and their functions:

- **startAll:** Ensures the system initializes only once after power-up.
- **i2c:** Controls the I2C communication with the MPU6050 sensor.
- **mpu6050:** Manages and retrieves data from the inertial sensor.
- **arctanCORDIC (two instances):** Computes the tilt angles on two axes using the CORDIC algorithm.
- **lowPassFilter (two instances):** Filters the angle signals to smooth out noise and fluctuations.
- **closeLoop (two instances):** Feedback controllers that compare measured angles with the level reference and generate correction commands.
- **servo (two instances):** Drives the servo motors according to the control signals.
- **inverterC and AND2b:** Used for logic control of the SDA line during I2C communication.



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Revision #2

Created 27 March 2025 18:54:11 by Caroline

Updated 27 March 2025 19:29:06 by Caroline