

block_0_0
block_0_39
block_1_29
block_2_19
block_3_9
block_3_49
block_4_39
block_5_29
block_6_19
block_7_9
block_7_49
block_8_39
block_9_29
block_10_19
block_11_9
block_11_49
block_12_39
block_13_29
block_14_19
block_15_9
block_15_49
block_16_39
block_17_29
block_18_19
block_19_9
block_19_49
block_20_39
block_21_29
block_22_19
block_23_9
block_23_49
block_24_39
block_25_29
block_26_19
block_27_9
block_27_49
block_28_39
block_29_29
block_30_19
block_31_9
block_31_49
block_32_39
block_33_29
block_34_19
block_35_9
block_35_49
block_36_39
block_37_29
block_38_19
block_39_9
block_39_49
block_40_39
block_41_29
block_42_19
block_43_9
block_43_49
block_44_39
block_45_29
block_46_19
block_47_9
block_47_49
block_48_39
block_49_29
in_14
out_4
out_44
The regulator keeps the
rail within tolerance while
the load steps from idle to
full draw; the loop
compensation trades
overshoot for settling time.
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the load steps from idle to full draw; the loop
compensation trades overshoot for settling time.
The regulator keeps the rail within tolerance while the load steps from
idle to full draw; the loop compensation trades overshoot for settling
time.
Sensor fusion:
accelerometer,
gyroscope and
magnetometer feed
an extended Kalman
filter whose
covariance is
re-seeded on every
calibration.
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gyroscope and magnetometer feed an
extended Kalman filter whose
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office affinity

office affinity

Waveform AV-To-Ty kerning

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whose covariance is re-seeded on every calibration.
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