Descriptions of the videos 2 to 26
UFO Doctor, Oct 1st, 2010

Info to video 2: SwissGyro V5_3 on test bench
UFO Doctor, Aug. 2nd, 2007
This video shows the behavior of the SwissGyro V5_3 on the test bench. Note the large range of pitch and roll (+/-60 Degrees) and the damping of the precession.

Info to video 3: SwissGyro V5_3 mounted on standard XUFO
UFO Doctor, Aug. 12th, 2007
This video show the first flight of a standard Silverlit XUFO equipped with the SwissGyro V5_3. Note the stability, also without manual remote control.
No flips, gyro remains stable also after a hard landing.

Info to video 4: Indoor with SwissGyro V5_3
UFO Doctor, Aug.17th, 2007, rev. Aug. 5th, 2008
This video shows the good stability. Indoor flight remains stable also without manual remote control. Note the reaction when the XUFO is touched: it returns to the horizontal position.
The SwissGyro presents 3 application levels:
- Level 1: Auto stable for learning flying indoor or outdoor without wind
- Level 2: Stable outdoor flight also at windy conditions
- Level 3: Full control, inclinations possible up to 45 degrees, similar to a steering with piezo angular velocity sensors.

The SwissGyro V5_4, produced 2008, is tuned for an angular sensitivity of about 12mV/degree. This allows both auto stable flight and pitch/roll up to 30 degrees

Info to video 7, 8 and 9: SwissGyro Serial Nr 12 at the university of Bern
UFO Doctor, June 20th, 2008
Sensor specifications of SwissGyro Serial Nr 12
Pitch: 11mV/degree, Roll: 12.7 mV/degree
The pilot is master student Reto S, the scenery is the University of Applied Sciences (HTI), Bern/Biel, Switzerland
Reto got frustrating experiences with the original Silverlit X-UFO and is happy now to fly with SwissGyro.

Info to video 10 and 11: SwissGyro Serial Nr 16 at the university of Bern
UFO Doctor, June 26th, 2008
Sensor specifications of SwissGyro Serial Nr 16
Pitch: 9.3 mV/degree, Roll: 10.2 mV/degree
Master student Markus L. pushes the X-UFO during flight in order to demonstrate the auto stability.
The scenery is the University of Applied Sciences (HTI), Bern/Biel, Switzerland

Info to video 17 to 20: SwissGyro Serial Nr 13, windy weather conditions
UFO Doctor, Aug. 4th, 2008
Sensor specifications of SwissGyro Serial Nr 13
Pitch: 12.7mV/degree, Roll: 16.2 mV/degree
The pilot is the experienced Hardy Buob, well known for building large-scale models; the scenery is the residence of the UFO Doctor at a very windy day.

The frame of the X-UFO was removed after flight Nr. 17 in order to reduce the disturbing effects of the heavy side winds.

Info to video 21: SwissGyro Serial Nr 13, dynamic flight,
UFO Doctor, Aug. 20th, 2008
Sensor specifications of SwissGyro Serial Nr 13
Pitch: 12.7mV/degree, Roll: 16.2 mV/degree
The frame of the X-UFO was removed in order to reduce the disturbing effects of side winds, and the X-UFO was not equipped with any Yaw sensor.

The pilot is the experienced Hardy Buob, well known for building large-scale models. Thank you for this video!

Info to video 22: VEDA at Technorama
UFO Doctor, April 3rd, 2009.
The pilot is Christoph Widmer, a young professional pilot flying Super puma helicopter for the Swiss army. The scenery is the dining room of Techorama, the science center of Winterthur, Switzerland.
VEDA invites every years the former students of "Akademikergemeinschaft", this time combined with a short lecture on X-UFO with SwissGyro after dinner.

Info to video 23 and 25: Yaw Sensor on Plottermeier-Mod
UFO Doctor, July 6th, 2009.
Video 23 and 24: Paul from UK is flying an X-UFO, equipped with his own Plottermeier-Mod and the Yaw-Sensor from the UFO Doctor (see "Angebot 4")

UFO Doctor, Sept 8th, 2009.
Video 25: Paul from UK is flying an X-UFO, equipped with his self-made SwissGyro from the kit "Angebot 3" and with the Yaw-Sensor "Angebot 4"

Info to video 26: Brushless P&P BL mod
UFO Doctor, Oct 1st, 2010
This is the first test flight with the brushless P&P mod, a cooperation between Paul (UK) and Peter (UFO-Doctor, CH)
Motors: Turnigy 2204
Propellers: Original Silverlit
ESC's: Roxxy 710 (with Quax software, V2, on my homepage)
Sensors: SwissGyro with Yaw sensor (see homepage)

The reactions on both RC and Gyro are very fast: The (servo) travel adjusts of the RC had to be limited to +/-50 % and the hall-sensors of the SG are bent up by 60 degrees.

This BL-X-UFO with a weight of 322 gram (with 3-Cell Lipo 600 mAh) is clearly over-motorized. At 12 V the current consumption is about 4A for hovering.

It runs with a 2-Cell 800mAh or a 3-Cell 600mAh, but a 3-Cell 900 mAh would be much better.