

Do you need help with interpreting the plots? See [here](#).

PX4 Quadrotor

Open 3D View

Open PID Analysis

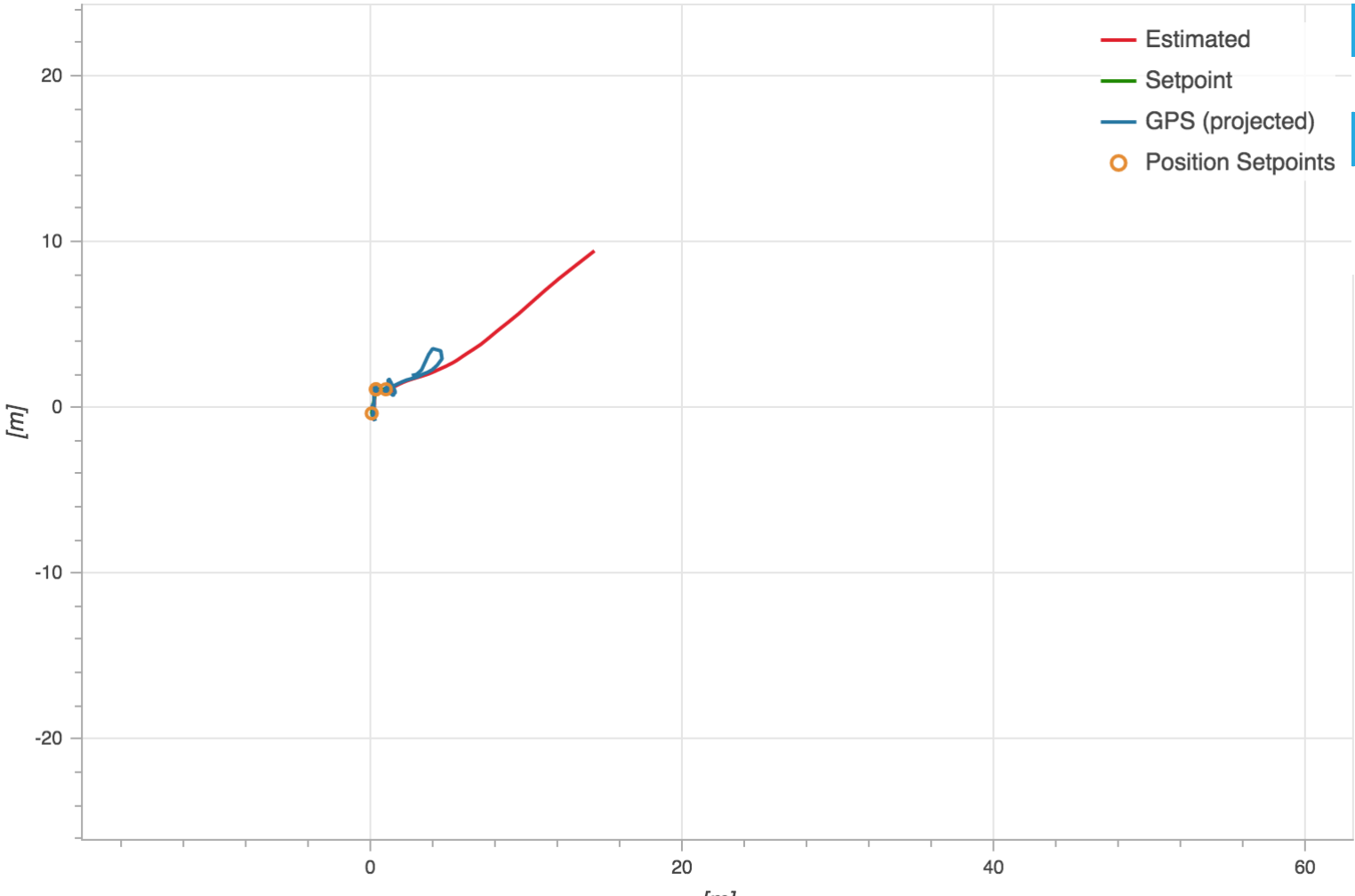
Airframe:	Lumenier QAV250 Quadrotor x (4009)
Hardware:	PX4_FMU_V5 (V540)
Software Version:	v1.9.2 (10690587)
OS Version:	NuttX, v7.28.0
Estimator:	EKF2
Logging Start ?:	14-09-2019 10:42
Logging Duration:	0:01:58
Vehicle Life Flight Time:	42 minutes 19 seconds
Vehicle UUID:	000200000000353436333138511900170034

Distance:	73.3 m
Max Altitude Difference:	46 m
Average Speed:	2.4 km/h
Max Speed:	80.4 km/h
Max Speed Horizontal:	18.9 km/h
Max Speed Up:	10.6 km/h
Max Speed Down:	78.6 km/h
Max Tilt Angle:	177.4 deg
Max Rotation Speed:	2081.3 deg/s
Average Current:	8.6 A
Max Current:	24.8 A

Add a detected error...

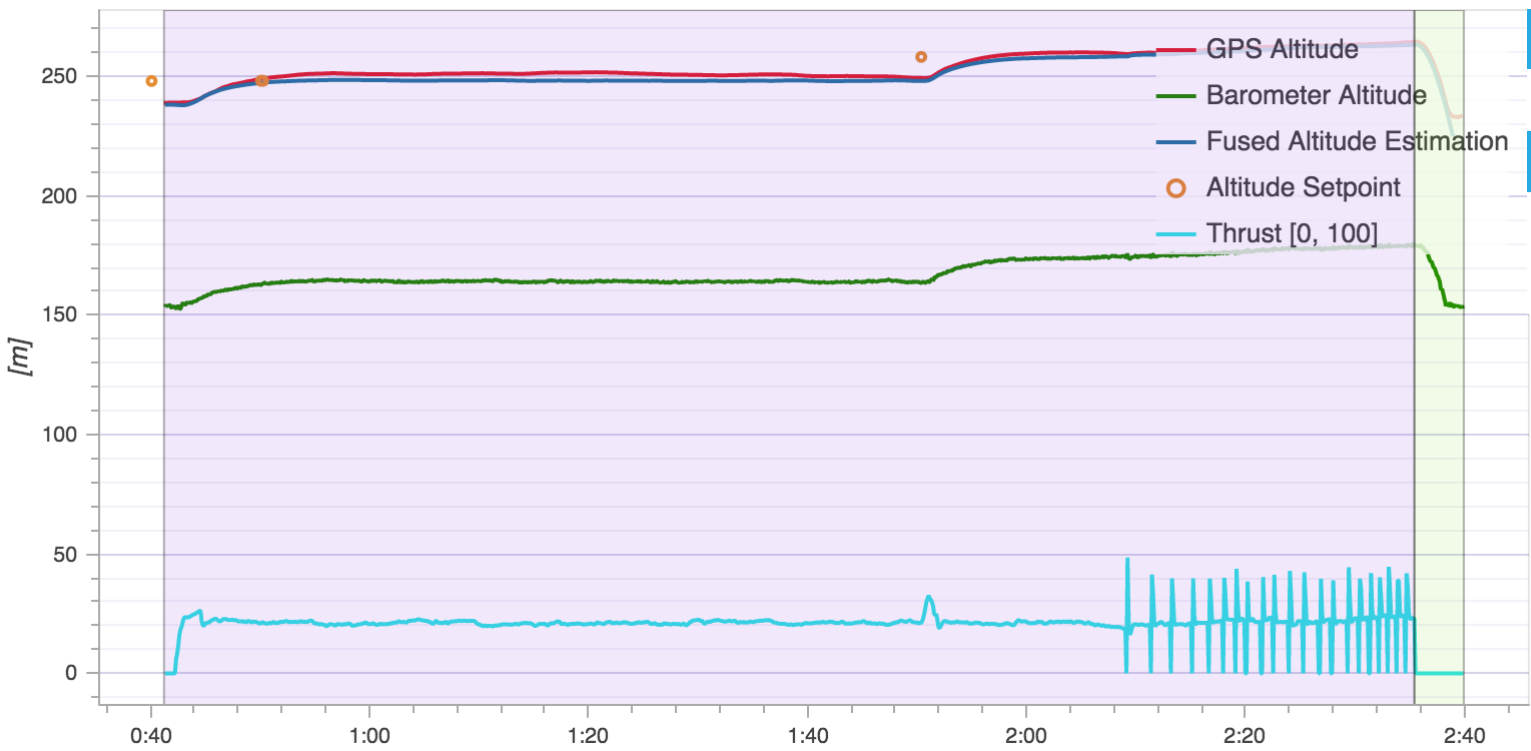


Leaflet | Imagery © Mapbox



[m]

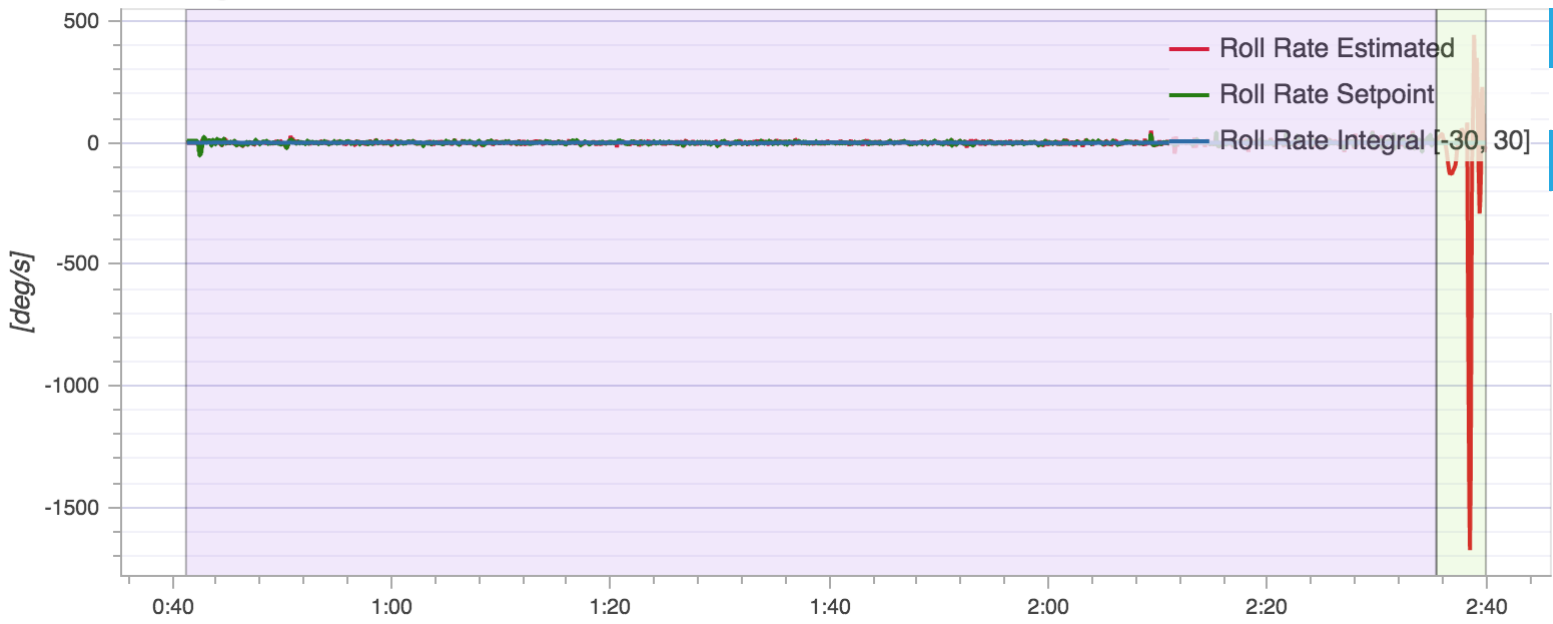
Altitude Estimate



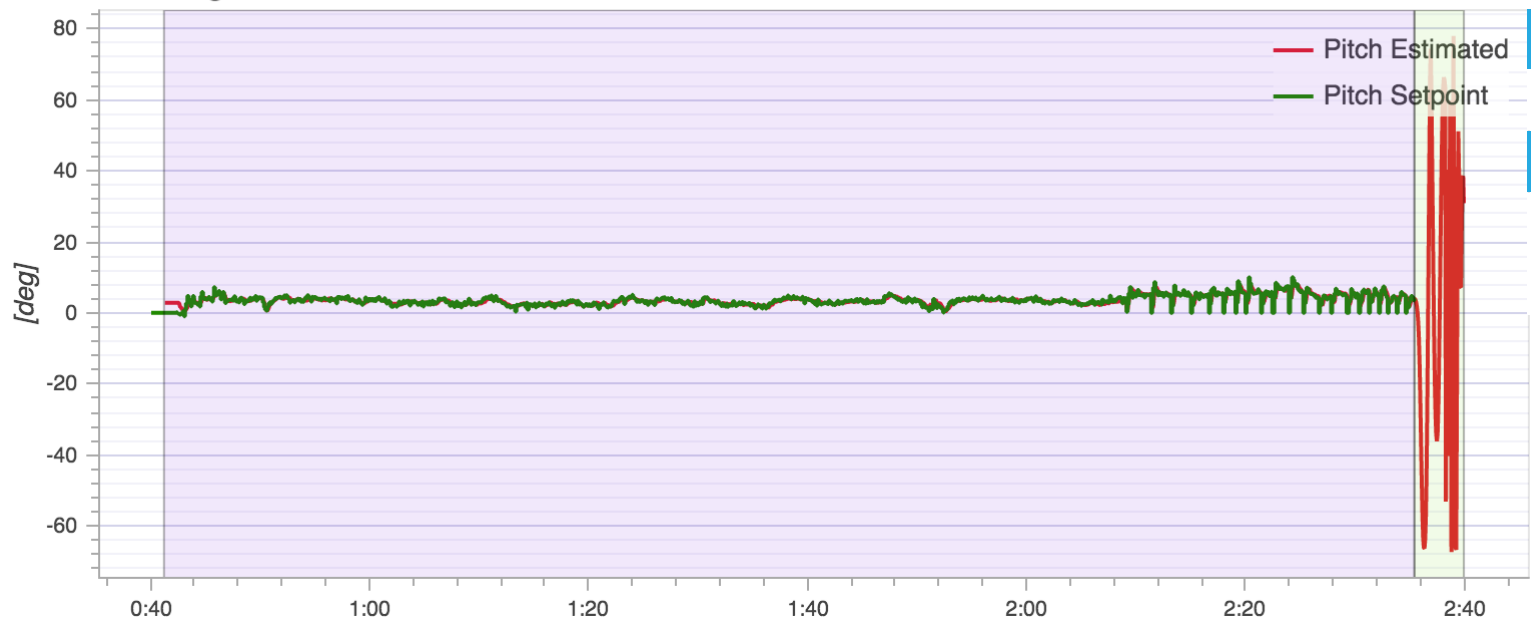
Roll Angle



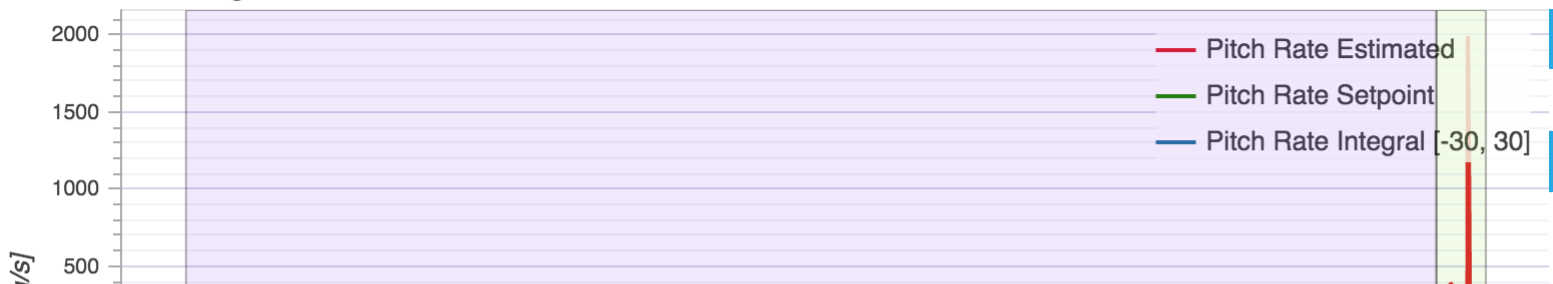
Roll Angular Rate

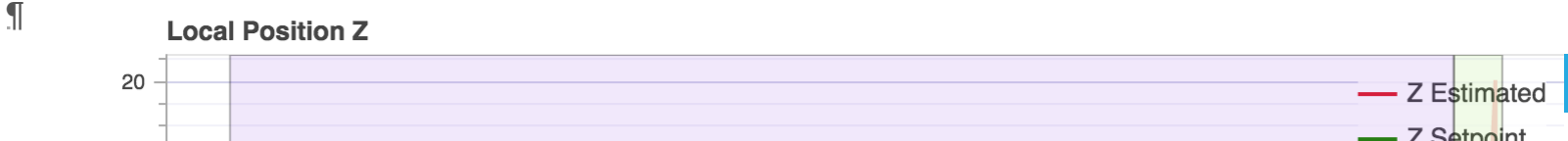
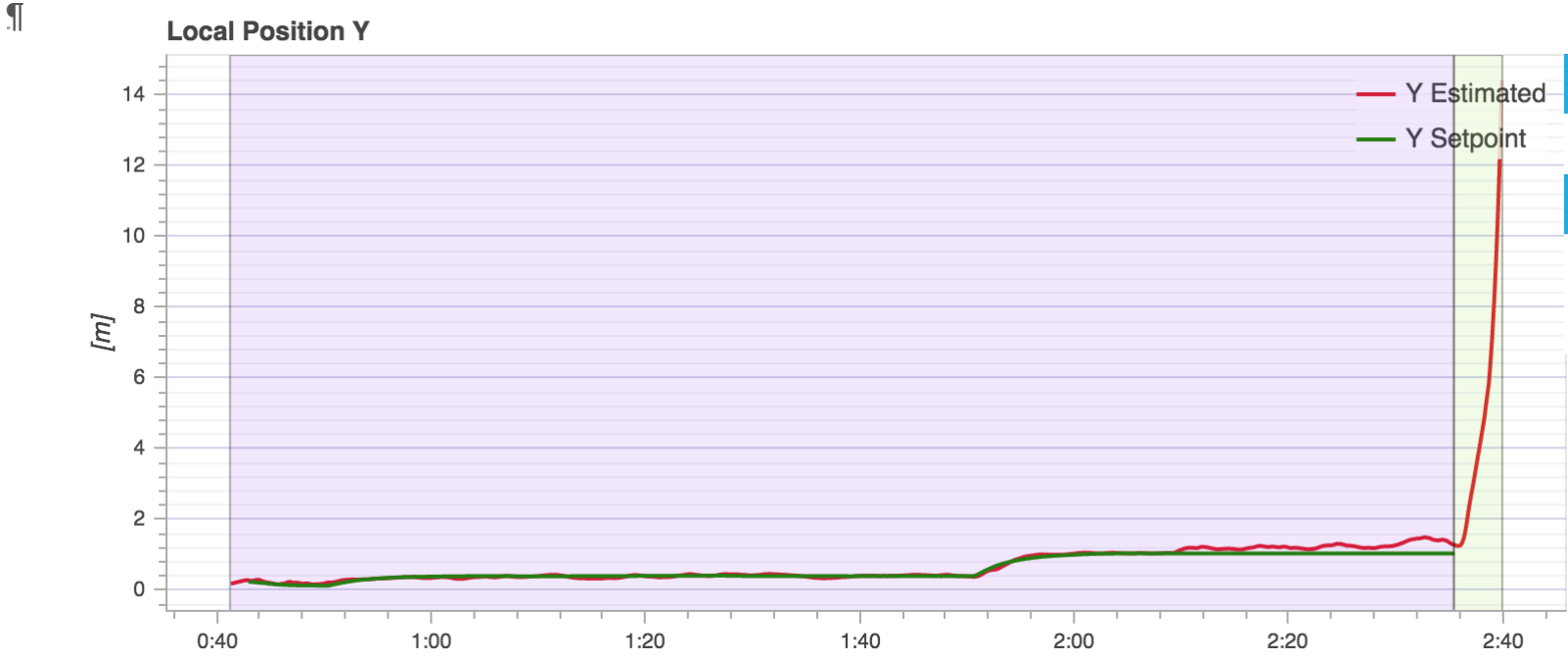
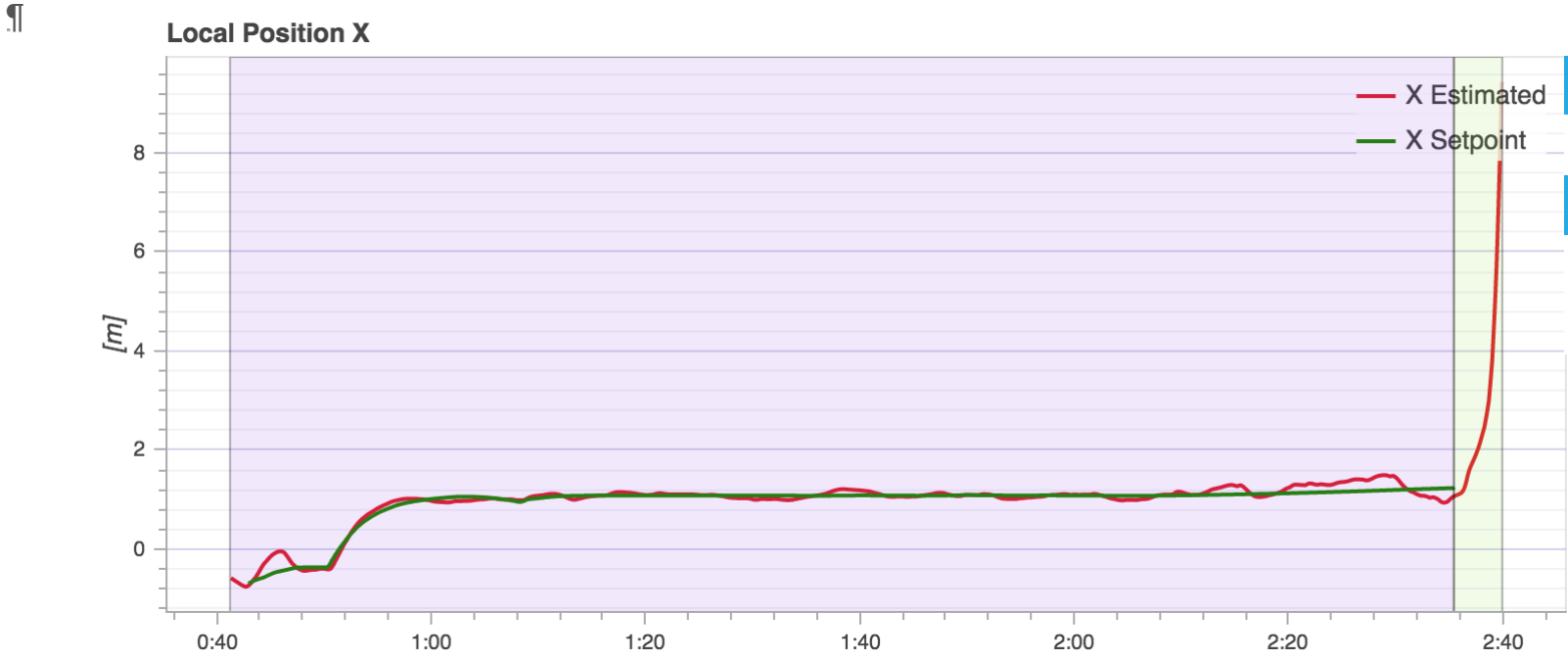
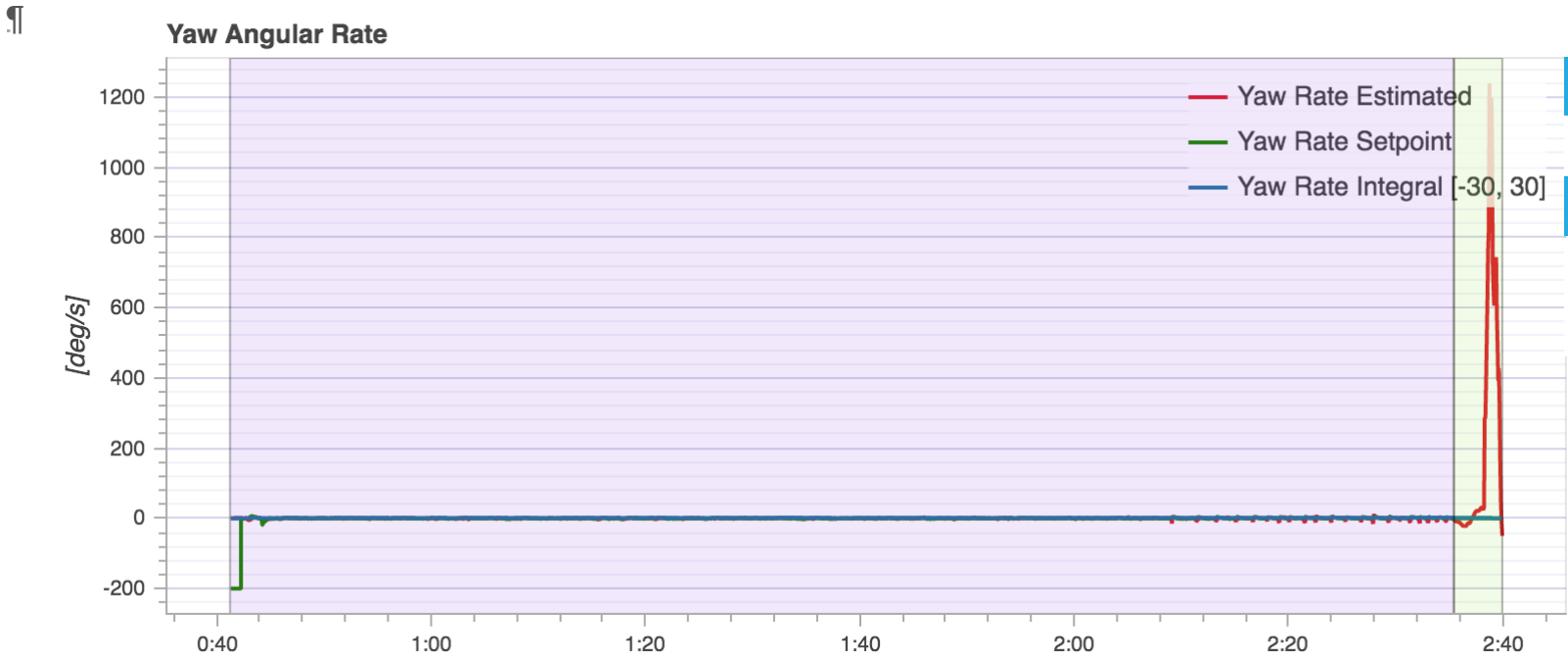
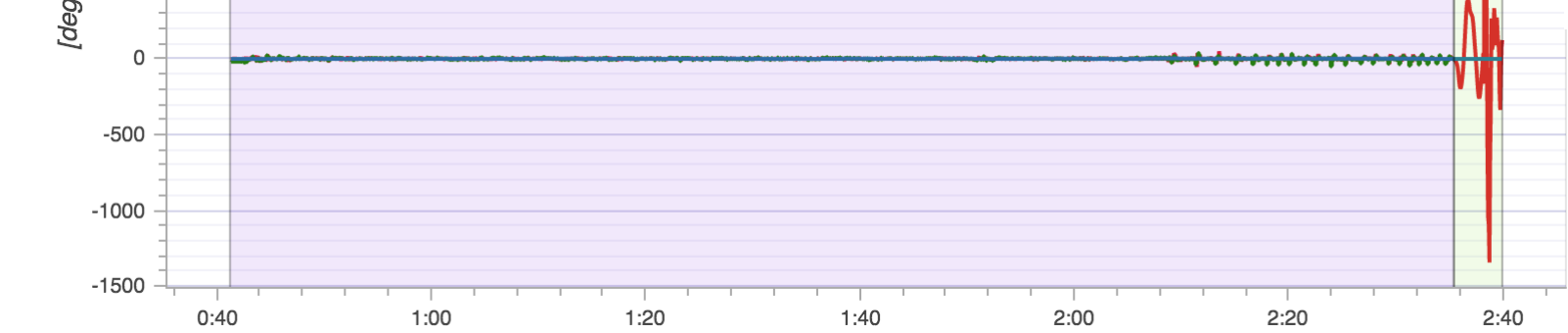


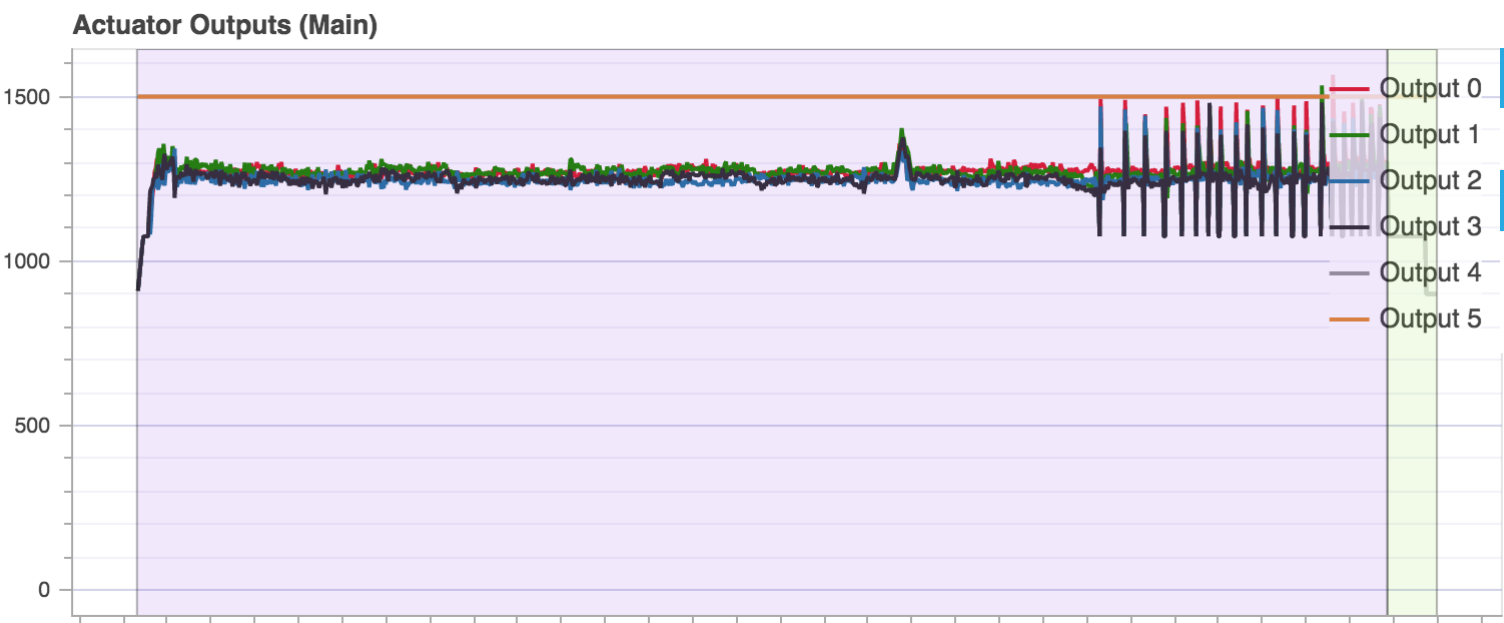
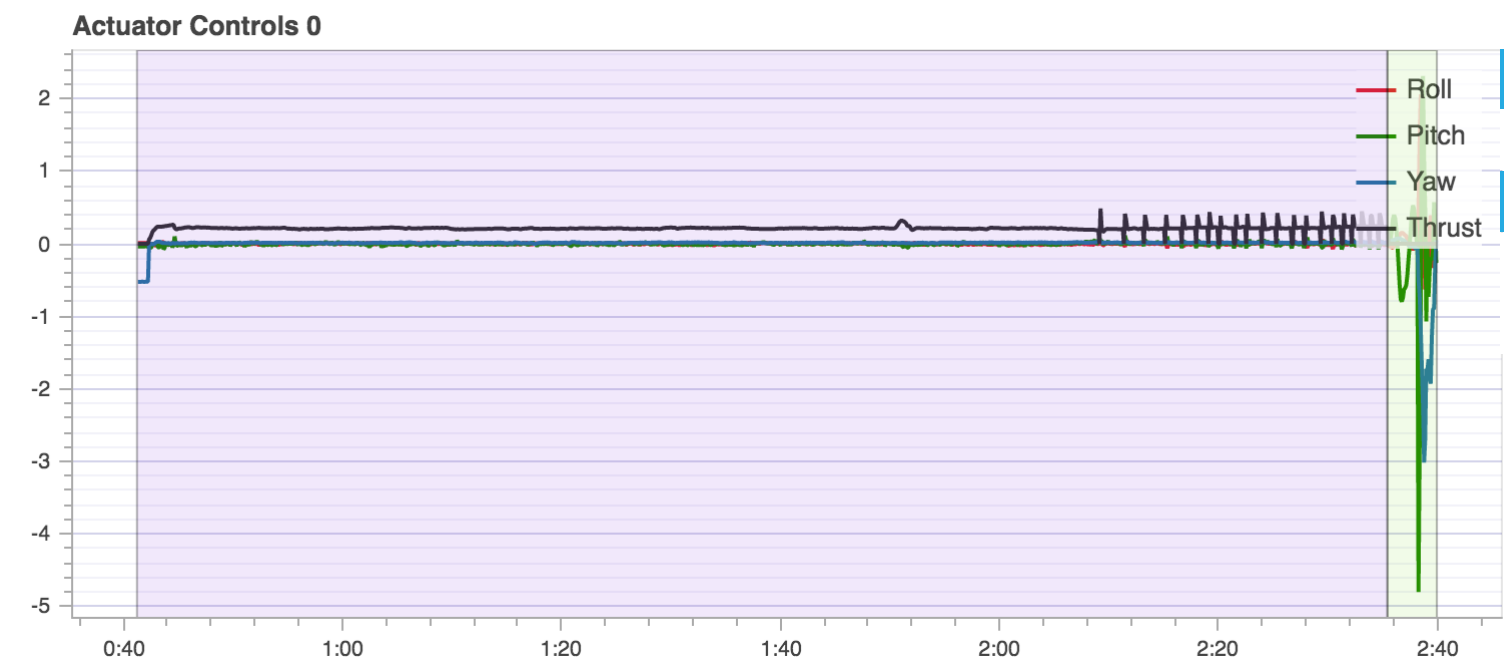
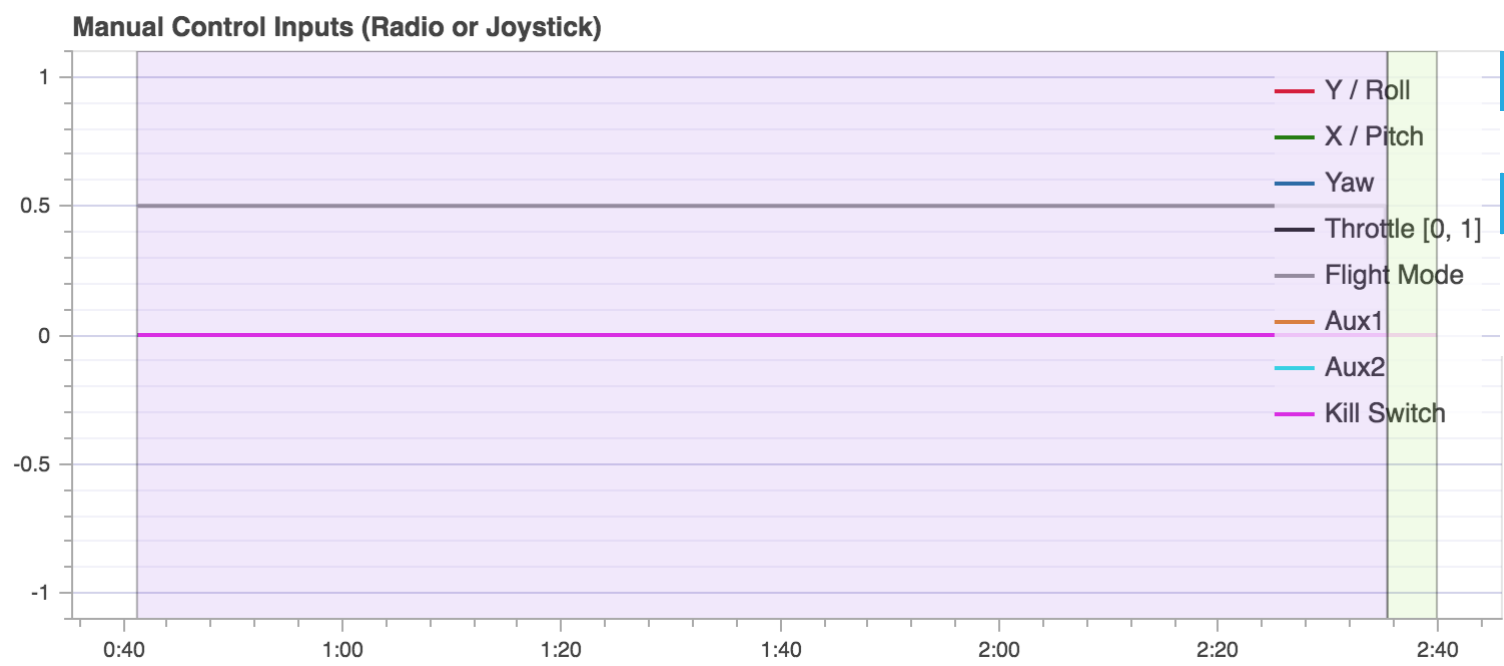
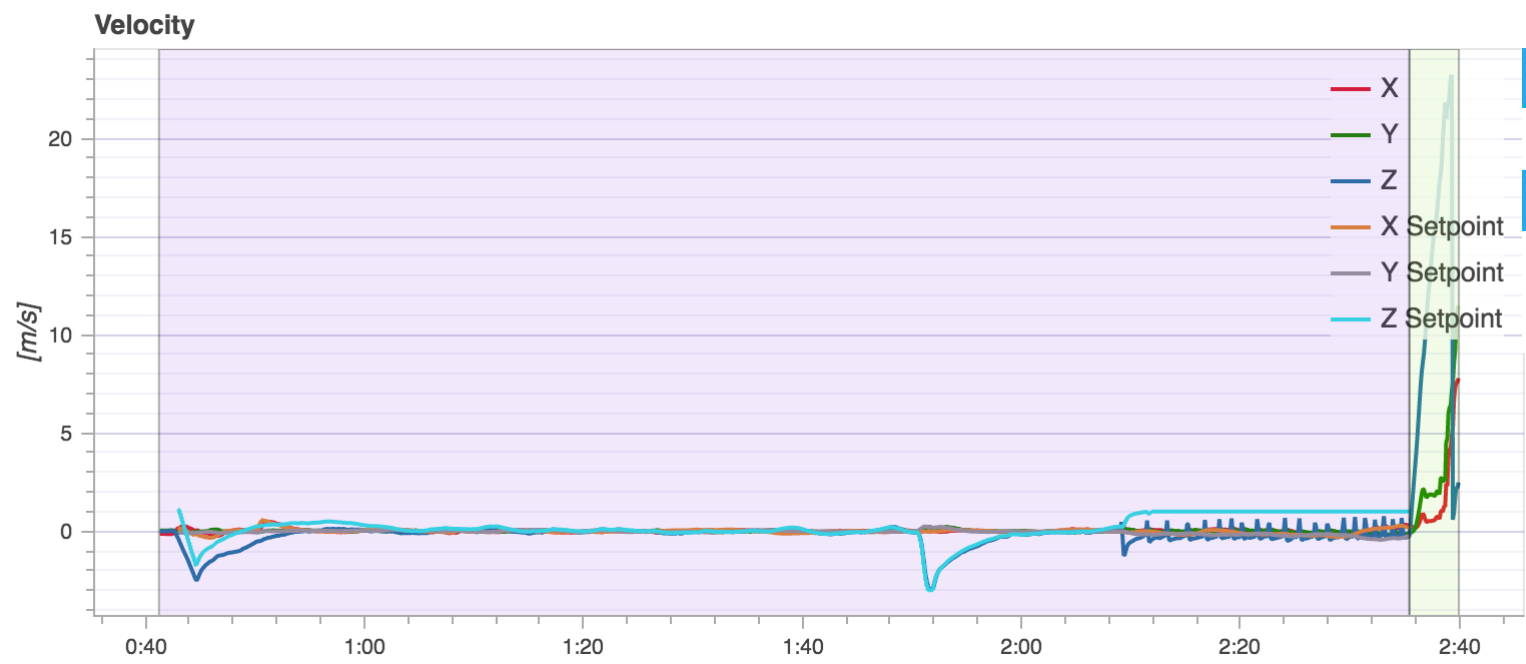
Pitch Angle

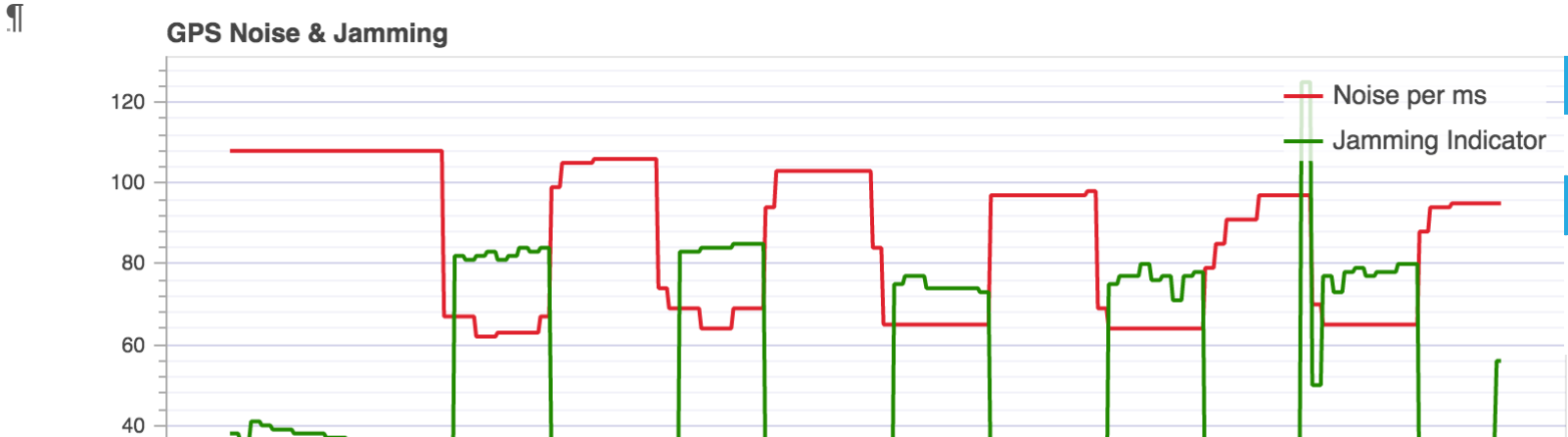
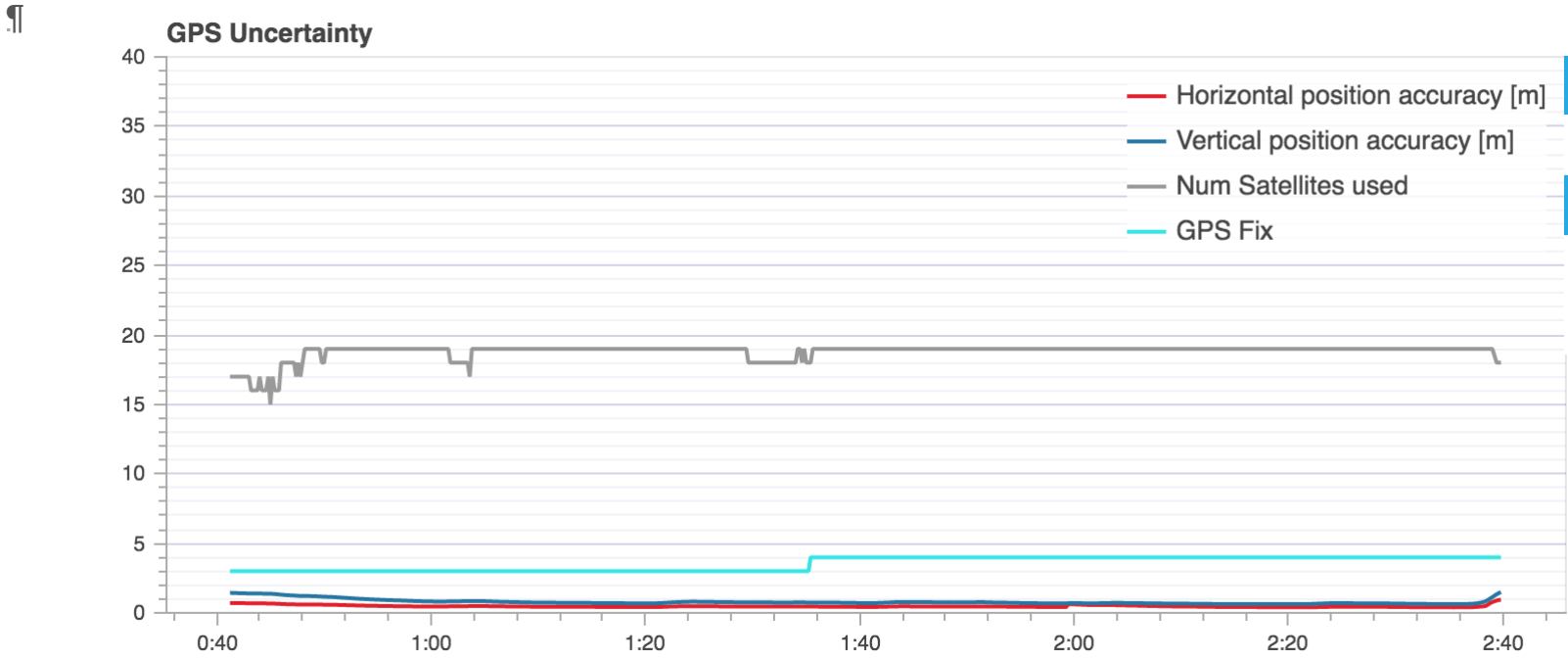
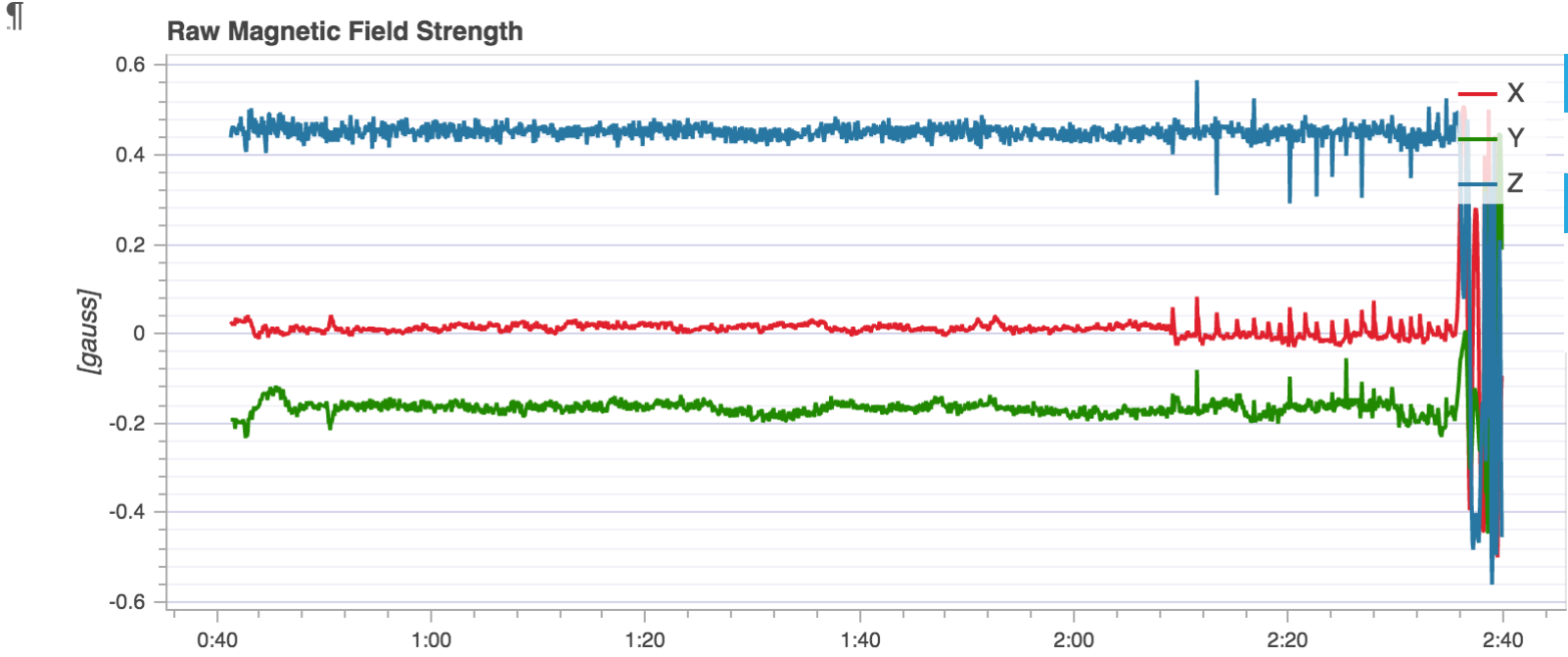
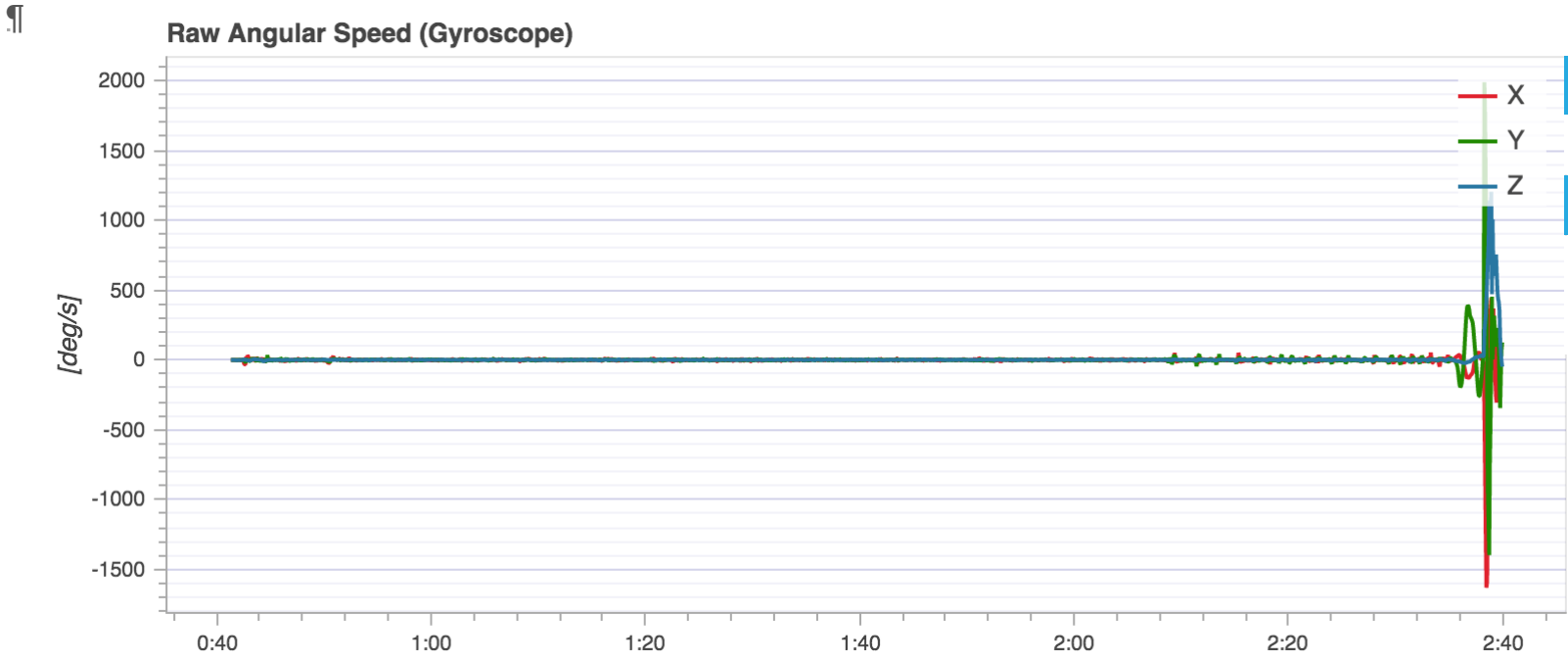
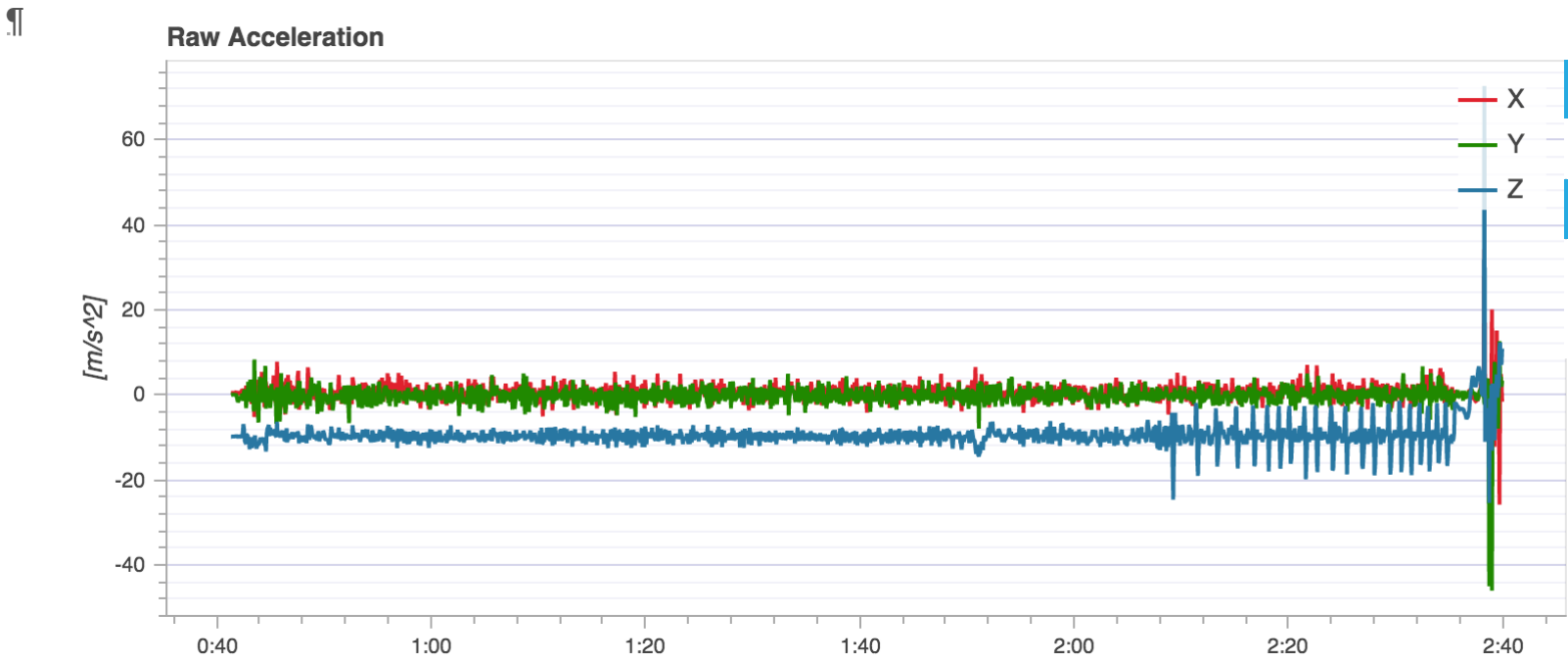


Pitch Angular Rate



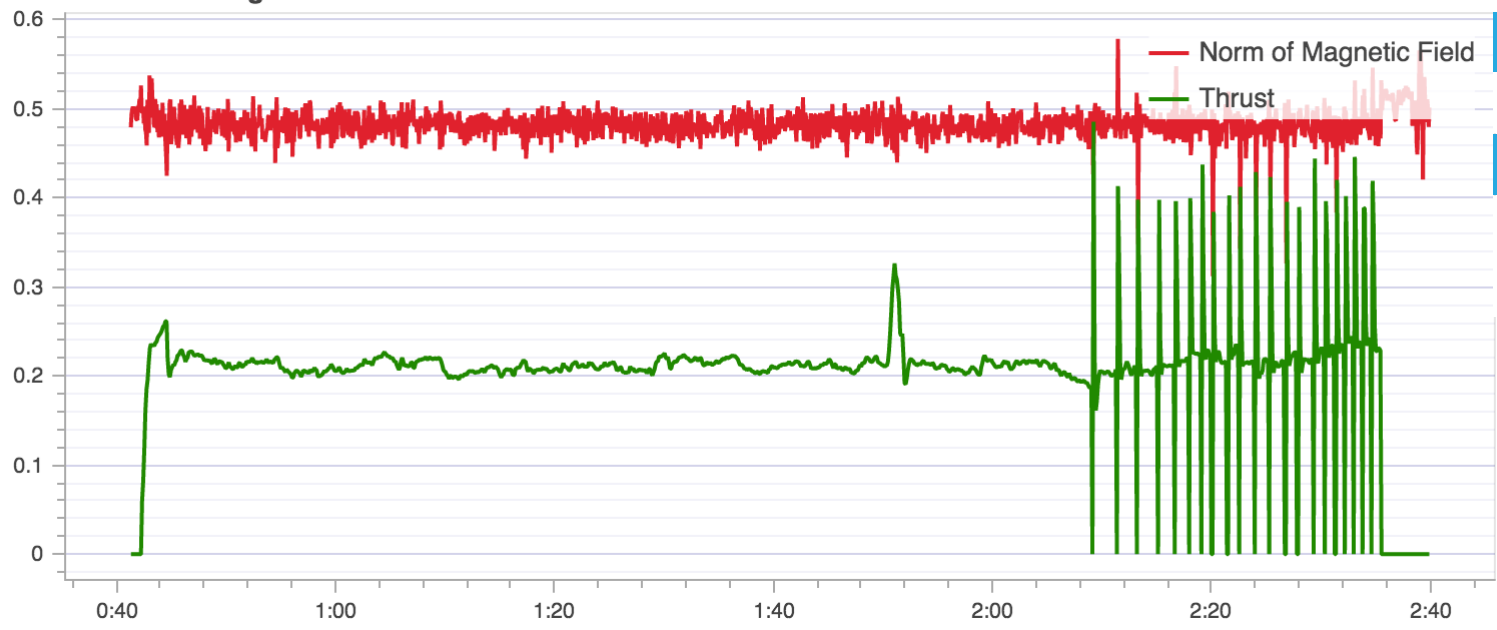




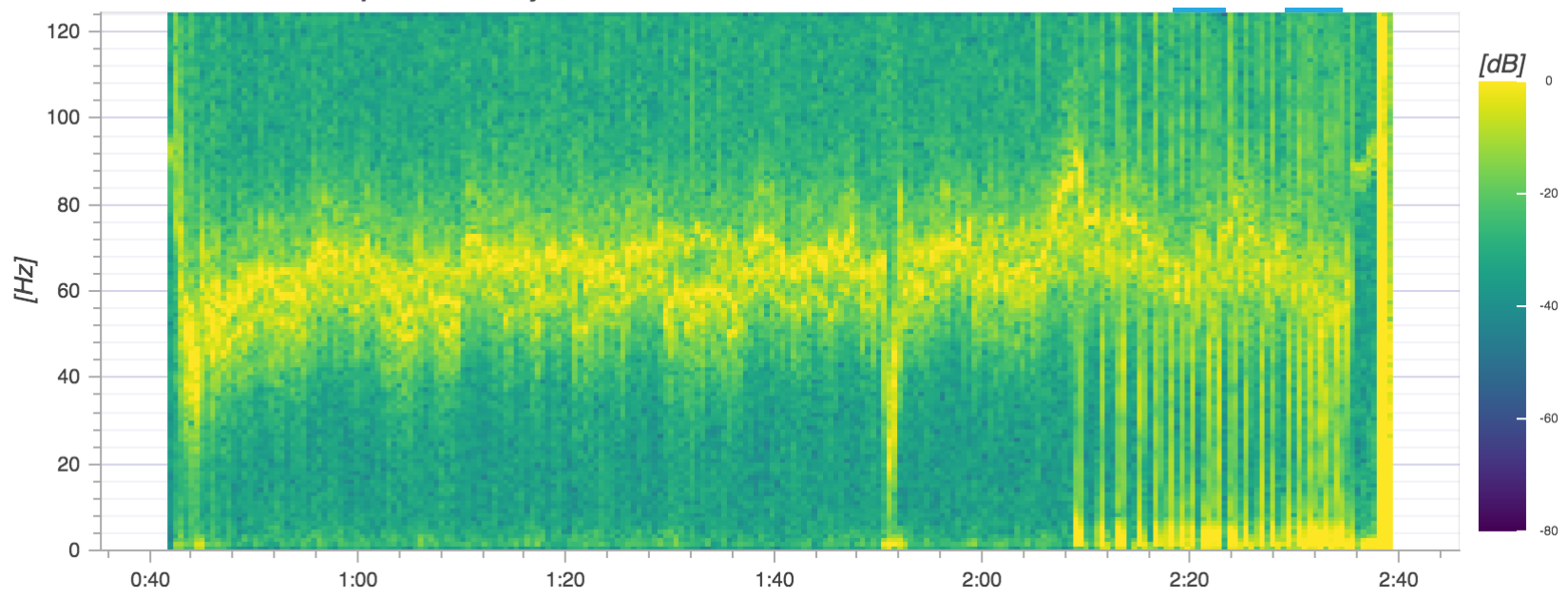




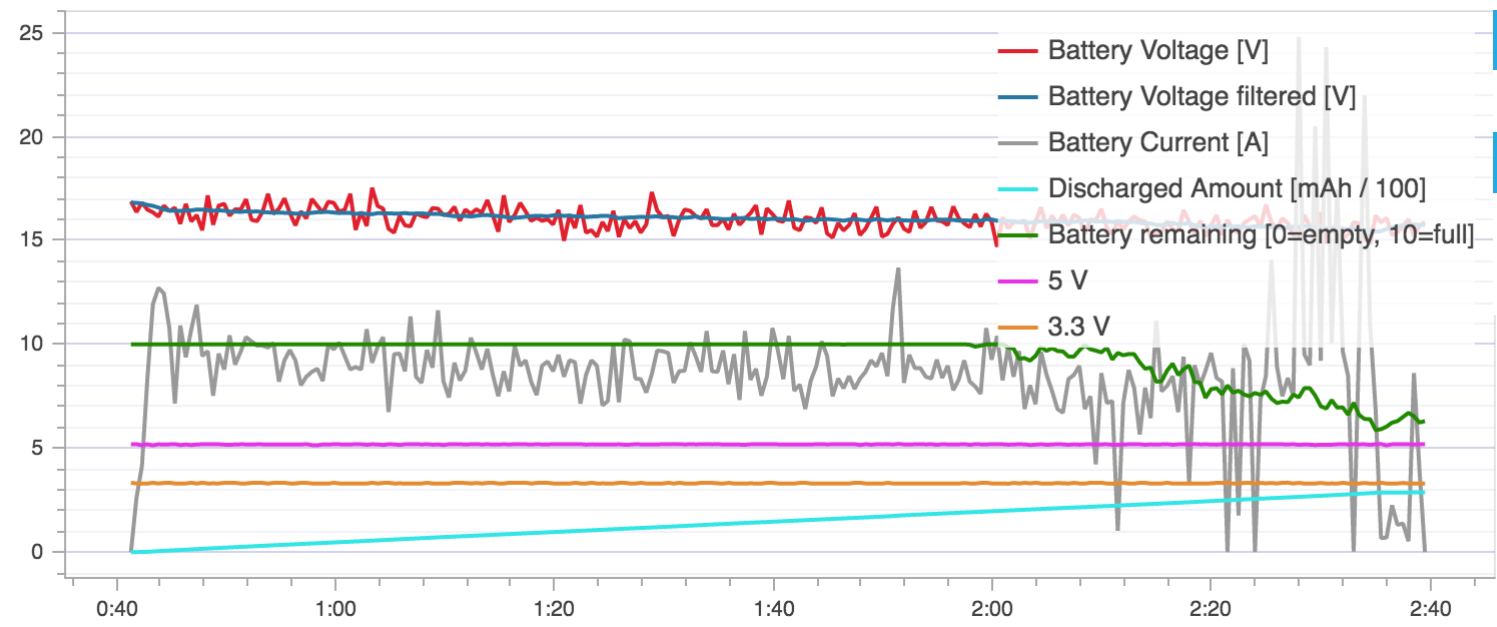
Thrust and Magnetic Field



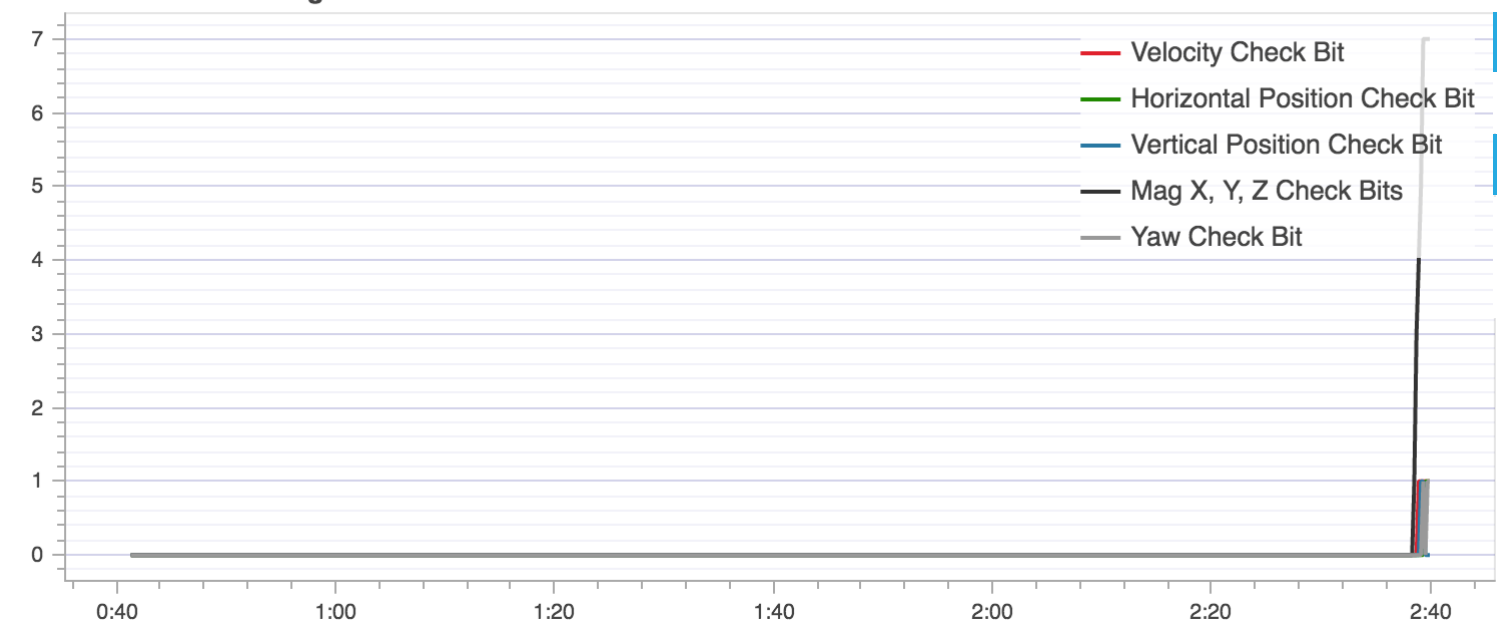
Acceleration Power Spectral Density



Power

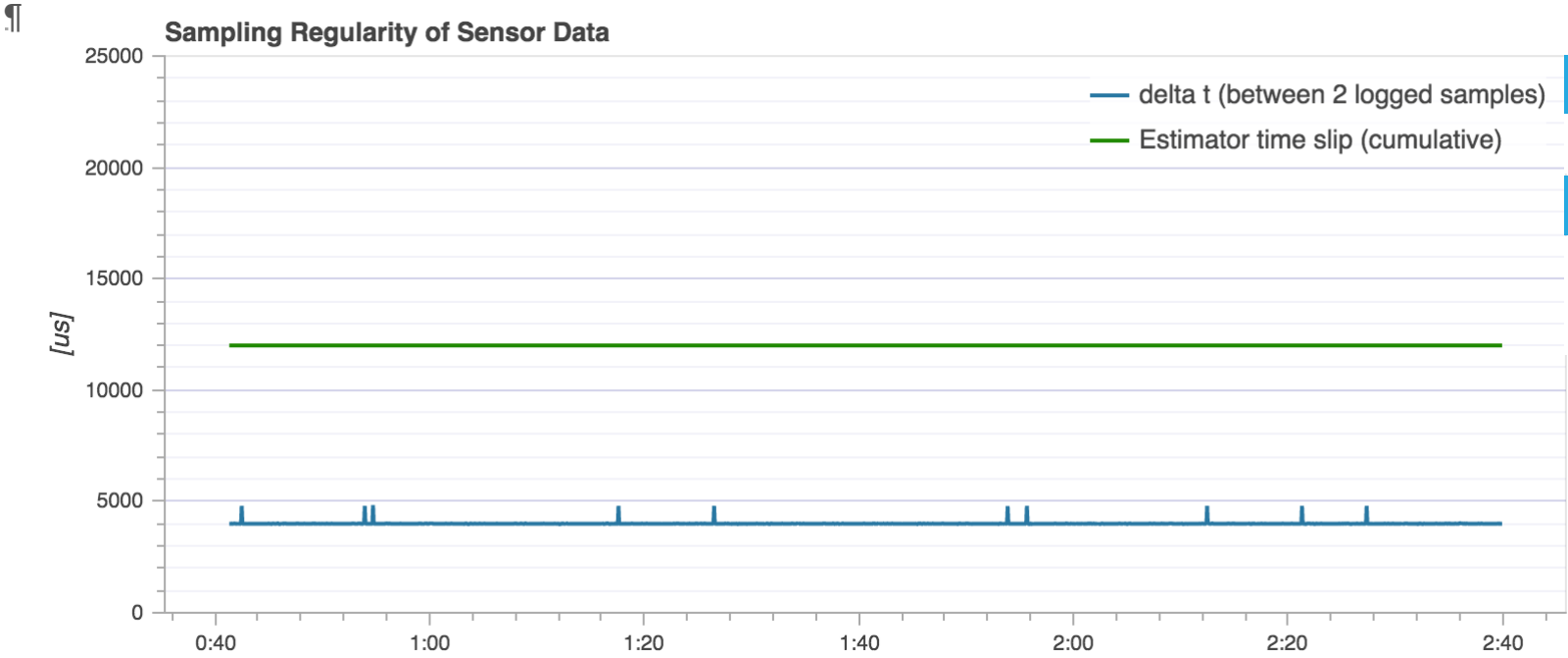
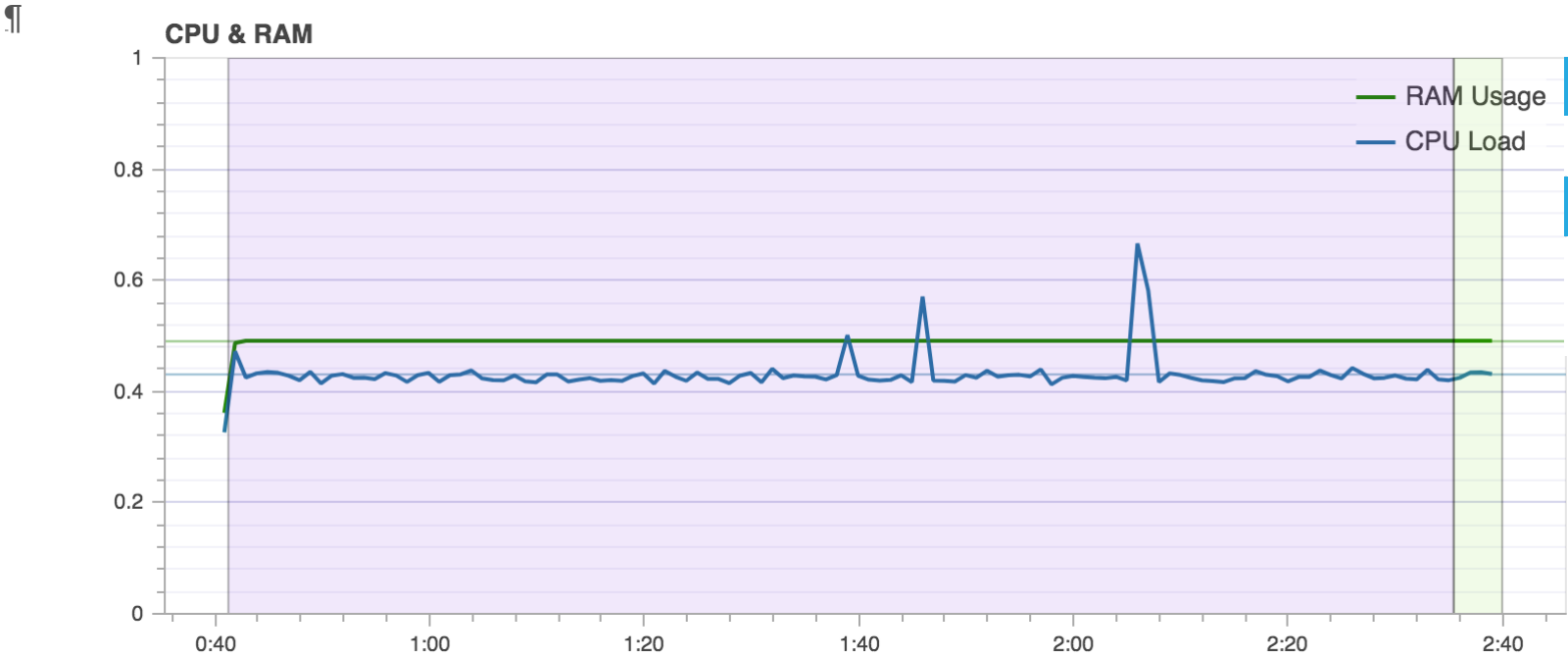
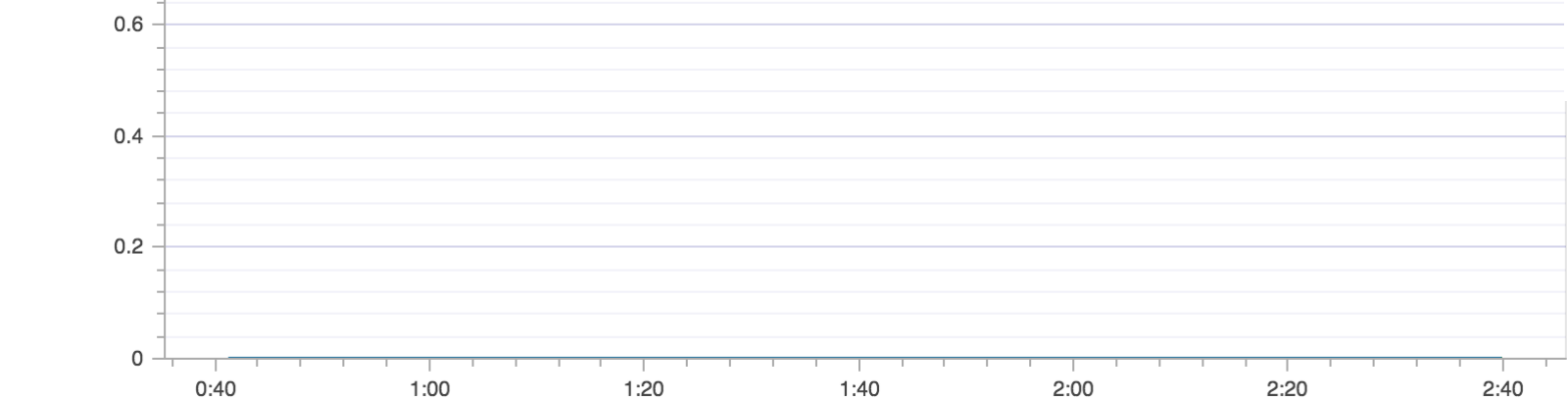


Estimator Watchdog



RC Quality





Non-default Parameters (except RC and sensor calibration)

#	Name	Value	Default	Min	Max	Description
0	BAT_A_PER_V	36.36751556	-1.0			Battery current per volt (A/V)
1	BAT_CNT_V_CURR	0.00080566	-1.0			Scaling from ADC counts to volt on the ADC input (battery
2	BAT_CNT_V_VOLT	0.00080566	-1.0			Scaling from ADC counts to volt on the ADC input (battery
3	BAT_N_CELLS	4	0			Number of cells
4	BAT_V_DIV	18.10000038	-1.0			Battery voltage divider (V divider)
5	BAT_V_EMPTY	3.75	3.5			Empty cell voltage (5C load)
6	CBRK_IO_SAFETY	22027	0	0	22027	Circuit breaker for IO safety
7	COM_ARM_MAG	0.15000000596046448				(unknown)
8	COM_DISARM_LAND	0	2.0			Time-out for auto disarm after landing
9	COM_FLIGHT_UUID	59	0	0		Next flight UUID
10	COM_FLTMODE1	6	-1			First flightmode slot (1000-1160)

Logged Messages

#	Time	Level	Message
0	0:00:03	ERROR	[pmw3901] driver start failed
1	0:00:03	WARNING	[bst] no devices found
2	0:00:41	WARNING	[mavlink] Not enough bandwidth to enable log streaming
3	0:00:41	ERROR	[mavlink] Not enough bandwidth to enable log streaming
4	0:02:39	WARNING	[ec/EKF] EKF baro hgt timeout - reset to baro

Show additional Data