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Vehicle Setup



Summary

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Firmware

BAT1_A_PER_V 15.39103031 Battery 1 current per volt (A/V)

BAT1_N_CELLS 3S Battery Number of cells for battery 1



Airframe

BAT1_V_CHARGED 4.00 V Full cell voltage (5C load)

BAT1_V_DIV 18.12207985 Battery 1 voltage divider (V divider)



Sensors

BAT1_V_EMPTY 3.00 V Empty cell voltage (5C load)



Radio

CAL_ACC0_ID 2162698 Accelerometer 0 calibration device ID

CAL_ACC0_PRIO Medium (Default) Accelerometer 0 priority



Flight Modes

CAL_ACC0_XOFF -0 m Accelerometer 0 X-axis offset

CAL_ACC0_YOFF -0 m Accelerometer 0 Y-axis offset



Power

CAL_ACC0_ZOFF 1 m Accelerometer 0 Z-axis offset



Motors

CAL_GYRO0_ID 2162698 Gyroscope 0 calibration device ID

CAL_GYRO0_PRIO Medium (Default) Gyroscope 0 priority



Safety

CAL_GYRO0_XOFF -0 m Gyroscope 0 X-axis offset

CAL_GYRO0_YOFF 0 m Gyroscope 0 Y-axis offset



Camera

CAL_GYRO0_ZOFF 0 m Gyroscope 0 Z-axis offset



Parameters

CAL_MAG0_ID 396817 Magnetometer 0 calibration device ID

CAL_MAG0_PRIO High Magnetometer 0 priority

CAL_MAG0_ROT No rotation Magnetometer 0 rotation relative to airframe

CAL_MAG0_XODIAG -0 Magnetometer 0 X-axis off diagonal scale factor

CAL_MAG0_XOFF -1 m Magnetometer 0 X-axis offset

CAL_MAG0_XSCALE 1 Magnetometer 0 X-axis scaling factor

CAL_MAG0_YODIAG 0 Magnetometer 0 Y-axis off diagonal scale factor



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Firmware



Airframe



Sensors



Radio



Flight Modes



Power



Motors



Safety



Camera



Parameters

CAL_MAG0_YODIAG	0	Magnetometer 0 Y-axis off diagonal scale factor
CAL_MAG0_YOFF	-0 m	Magnetometer 0 Y-axis offset
CAL_MAG0_YSCALE	1	Magnetometer 0 Y-axis scaling factor
CAL_MAG0_ZODIAG	0	Magnetometer 0 Z-axis off diagonal scale factor
CAL_MAG0_ZOFF	0 m	Magnetometer 0 Z-axis offset
CAL_MAG0_ZSCALE	1	Magnetometer 0 Z-axis scaling factor
COM_FLIGHT_UUID	50	Next flight UUID
EKF2_ANGERR_INIT	0.573 deg	1-sigma tilt angle uncertainty after gravity vector alignment
EKF2_GBIAS_INIT	0.01 rad/s	1-sigma IMU gyro switch-on bias
EKF2_MAG_TYPE	Magnetic heading	Type of magnetometer fusion
FW_AIRSPD_MAX	3.0 m/s	Maximum Airspeed (CAS)
FW_AIRSPD_MIN	0.0 m/s	Minimum Airspeed (CAS)
FW_AIRSPD_TRIM	1.0 m/s	Cruise Airspeed (CAS)
LND_FLIGHT_T_HI	4	Total flight time in microseconds
LND_FLIGHT_T_LO	1067844732	Total flight time in microseconds
MAV_TYPE	Ground rover	MAVLink airframe type
MIS_LTRMIN_ALT	0.0 m	Minimum Loiter altitude
MIS_TAKEOFF_ALT	0.0 m	Take-off altitude
NAV_ACC_RAD	0.5 m	Acceptance Radius
NAV_FW_ALT_RAD	1000.0 m	FW Altitude Acceptance Radius
NAV_LOITER_RAD	2.0 m	Loiter radius (FW only)
PWM_AUX_OUT	1234	PWM channels used as ESC outputs



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Firmware

PWM_AUX_OUT 1234 PWM channels used as ESC outputs

PWM_MAIN_DISARM 1500 us PWM main disarmed value



Airframe

PWM_MAIN_OUT 1234 PWM channels used as ESC outputs



Sensors

RC1_MAX 2016 us RC channel 1 maximum

RC1_MIN 992 us RC channel 1 minimum



Radio

RC1_TRIM 1538 us RC channel 1 trim



Flight Modes

RC2_MAX 2017 us RC channel 2 maximum

RC2_MIN 993 us RC channel 2 minimum



Power

RC2_TRIM 1509 us RC channel 2 trim



Motors

RC3_MAX 2018 us RC channel 3 maximum

RC3_MIN 993 us RC channel 3 minimum



Safety

RC3_TRIM 1501 us RC channel 3 trim



Camera

RC4_MAX 2017 us RC channel 4 maximum

RC4_MIN 993 us RC channel 4 minimum



Parameters

RC4_TRIM 1504 us RC channel 4 trim

RC_CHAN_CNT 8 RC channel count

RC_MAP_FLTMODE Channel 5 Single channel flight mode selection

RC_MAP_PITCH Channel 2 Pitch control channel mapping

RC_MAP_ROLL Channel 1 Roll control channel mapping

RC_MAP_THROTTLE Channel 3 Throttle control channel mapping

RC_MAP_YAW Channel 4 Yaw control channel mapping

SYS_AUTOSTART 50000 Auto-start script index