

en/EasySetup/EasySetup

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Inhaltsverzeichnis

<u>1 Overview -> Easy Setup</u>	1/11
<u>2 Name of the configuration</u>	2/11
<u>3 Enable Altitude control</u>	3/11
<u>3.1 Setpoint</u>	3/11
<u>3.2 Stick neutral point</u>	4/11
<u>3.3 Auto Start/Land Channel</u>	4/11
<u>4 GPS</u>	6/11
<u>4.1 GPS Mode Control</u>	6/11
<u>4.2 Dynamic PositionHold</u>	7/11
<u>4.3 ComingHome Altitude</u>	7/11
<u>5 Carefree control</u>	9/11
<u>5.1 Teachable CareFree</u>	9/11
<u>6 Mixer-SETUP</u>	11/11

1 Overview -> Easy Setup

Easy Setup

Name of configuration:

☒ Enable Altitude control

Setpoint: Mode: Vario altitude contr
Stick neutral: 0 - automatic 127 - middle position
Auto Start/Land Channel:

GAS:

☒ GPS

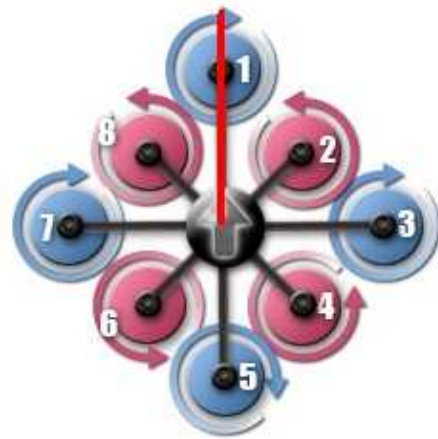
GPS Mode Control:
☒ Dynamic Position Hold
Coming Home Altitude: [m] 0 - disabled

Carefree control:

☒ Teachable Carefree

Mixer-SETUP

 Load...



2 Name of the configuration

You can set and save up to 56 different settings (Parametersets) in your copter.
If needed a personal name you can enter here.

Name of configuration:

In the basic settings the names are:

- Parameterset 1 => *Fast*
- Parameterset 1 => *Agile*
- Parameterset 1 => *Easy*
- Parameterset 1 => *Easy*
- Parameterset 1 => *Easy*

3 Enable Altitude control

Here you can activate / deactivate the barometric altitude sensor on the FlightCtrl.

- => altitude sensor deactivated

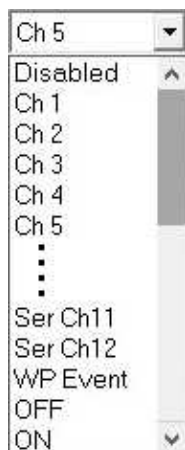
=> altitude sensor activate

If the barometric altitude sensor is deactivated you have to hold the altitude of the copter the whole time manually.

Only if the sensor is activated you can use the function [AltitudeHold](#) and activate this e.g. via a switch on your transmitter.

Then the copter can hold the altitude automatically.

3.1 Setpoint



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With the *Setpoint* you can use e.g. a channel to activate the function [AltitudeHold](#) via your transmitter. Or you can set it e.g. to ON. Then the function [AltitudeHold](#) is the whole time ON.

- ◆ **Disabled**

[AltitudeHold](#) disabled

- ◆ **Ch1 ... Ch16**

Channel 1-16 => This is the channel you also use on your transmitter with a 2way switch to switch this function ON/OFF

- ◆ **Ser Ch1 ... Ser Ch12**

Serial channel 1-12 => You can use a serial channel e.g. via your computer.

- ◆ **WP Event**

Please do not use

- ◆ **OFF**

[AltitudeHold](#) disabled

- ◆ **ON**

[AltitudeHold](#) activated

- **Function**

If the function [AltitudeHold](#) is activated the barometric altitude sensor will control the motors and the altitude.

Following applies:

- ◆ Throttle stick centered => Copter will hold the current altitude
- ◆ Throttle stick up => Copter goes up
- ◆ Throttle stick down => Copter goes down

When you move the throttle stick only a little bit up/down the copter will go up/down slow. Move the throttle stick more and the copter will go up/down faster.

3.2 Stick neutral point

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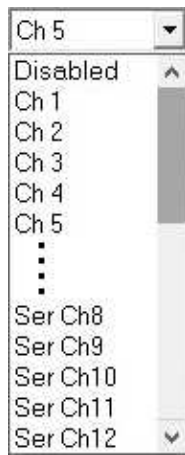
The *Stick neutral point* is the point where the throttle stick is centered. Here you can set a value or you center your stick and "click" on the green "Gas" symbol to set the right value.

- **INFO**

Depending on the transmitter you use the throttle stick will center automatically or not.

If the throttle stick will center automatically it is perfect to use the function [AltitudeControl](#) => Activate the function [AltitudeHold](#) and center the throttle stick. Now the copter will hold automatically the current altitude. If your throttle stick can not center automatically you have to move it manually to the center place. Please not that if the stick is not centered the copter can climb up/down slow (or faster) depending on the stick position.

3.3 Auto Start/Land Channel



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Set here a free channel for the function *Auto Start/Land* and use it with a 2way switch on your transmitter.

◆ Disabled

◇ Auto Start/Land disabled

◆ Ch1 ... Ch16

◇ Kanal 1-16 => This is the channel you also use on your transmitter with a 2way switch to use this function

● **Function**

The 2way switch on your transmitter use only 2 positions:

◆ Switch OFF => Position LAND

◆ Switch ON => Position START

How to use	
Auto-START - Your switch is in position OFF (LAND) - activate Function AltitudeHold - start the motors - center the throttle stick slow - move the 2way switch to ON (Start) (the switch will stay here for the flight!) - The motors will turn now faster and the copter lift up slow - and hold the altitude in ~ 1-2m - fly your copter as you want	Auto-LAND - fly the copter back to the landing place - center the throttle stick - move now the 2way switch back to OFF (Land) (the switch will now stay here!) - the copter goes down and land directly -> On the ground the motors will turn a little slower - switch off the motors

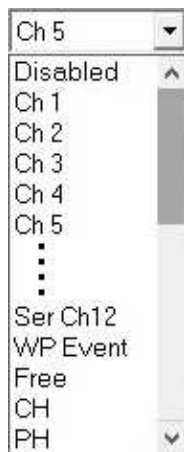
4 GPS

Activate or deactivate here your GPS.

- ☐ GPS => GPS deactivated
- ☒ GPS => GPS activated

Only with activated GPS you can use and switch functions like [ComingHome](#) or [PositionHold](#).

4.1 GPS Mode Control



- GPS Mode Control: 

Here you can set a channel for a 3way switch to switch the functions [ComingHome](#) and [PositionHold](#). Or you can set e.g. the function [ComingHome](#) or [PositionHold](#) still ON.

- ◆ **Disabled**

GPS-Function deactivated

- ◆ **Ch1 ... Ch16**

Channel 1-16 => This is the channel you also use on your transmitter with a 3way switch to use this function

- ◆ **Ser Ch1 ... Ser Ch12**

Serial channel 1-12 => You can use a serial channel e.g. via your computer.

- ◆ **WP Event**

Do not use

- ◆ **Free**

GPS-Function deactivated

- ◆ **CH**

Function [PositionHold](#) is still active

- ◆ **PH**

Function [ComingHome](#) is still active

- **Function**

Set here a free channel and use this channel on your transmitter with a free 3way switch.

- ◆ 3way switch OFF
=> GPS Function deactivated
- ◆ 3way switch centered
=> GPS Function [PositionHold](#) is activ -> The copter will hold the current place
- ◆ 3way switch ON
=> GPS Function [ComingHome](#) is activ -> The copter will fly back with 8m/s to the place where you start and lift off the copter ([HomePosition](#))

4.2 Dynamic PositionHold

- Here you can expand the function [PositionHold](#) with the function *DynamicPositionHold*.

- ☐ Dynamic PositionHold => DynamicPositionHold deactivated
- ☒ Dynamic PositionHold => DynamicPositionHold activated

Function

With activated function [PositionHold](#) the copter will hold automatically the current place. To fly to a other place move the Nick/Roll stick on your transmitter. During this you can now use the function *DynamicPositionHold*.

- ◆ **WITHOUT *DynamicPositionHold***
If you move the Nick-/Roll sticks to fly to a other position, the function [PositionHold](#) is deactivated automatically for the time you use the sticks.
Here you have a fast movind to change the position. But the copter can also fly a little bit over the place where you will stop the copter.
This depends on your handling of the sticks.
- ◆ **WITH *DynamicPositionHold***
When you now move the Nick-/Roll stick to change the position of the copter, the function [PositionHold](#) is not deactivated. Now you move with the sticks a *Target Point* - a point the copter will follow.
During this the copter is flying smoother and you can control it easier.

4.3 ComingHome Altitude

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For the function [ComingHome](#) and [FailSafe](#) you can set here an "safety" altitude. If you use then the function [ComingHome](#) or in an case of an [FailSafe](#) the copter will use this altitude to fly back to the place where you start the copter ([HomePosition](#)).

You can also deactivate this with a "0".

If you then use the function [ComingHome](#) or in case of an [FailSafe](#) the copter will hold the current position and fly back to the place where you start the copter ([HomePosition](#)).

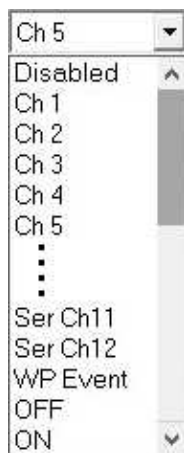
- **Function**

Activate the function [ComingHome](#). The copter will now directly fly back. During this the copter will climb up/down to the set altitude.

If the signal is lost and the function [FailSafe](#) is active the copter will first go up/down to the set altitude and fly then back.

More informations about the Function [FailSafe](#) you can read here: [FailSafe](#).

5 Carefree control



- **Carefree control:** Disabled

For the function [CareFree](#) you can set here a free channel.

- ◆ **Disabled**

[CareFree](#) deactivated

- ◆ **Ch1 ... Ch16**

Channel 1-16 => This is the channel you also use on your transmitter with a 2way switch to switch this function ON/OFF

- ◆ **Ser Ch1 ... Ser Ch12**

Serial channel 1-12 => You can use a serial channel e.g. via your computer.

- ◆ **WP Event**

Do not use

- ◆ **OFF**

Function [CareFree](#) deactivated

- ◆ **ON**

Function [CareFree](#) activated

- **Function**

Set here a free channel and set this channel also on a free 2way switch on your transmitter. Then you can use this function too:

- ◆ 2way switch OFF

=> Function [CareFree](#) deactivated

- ◆ 2way switch ON

=> Function [CareFree](#) activated

More informations about the function [CareFree](#) you can find here: [CareFree](#).

5.1 Teachable CareFree

- ☐ **Teachable Carefree** => Teachable CareFree deactivated

☒ **Teachable Carefree** => Teachable CareFree activated

- With *Teachable CareFree* the function [CareFree](#) is easier to use.
Depending on the distance to the starting point you can use the function [CareFree](#) now in 2 different ways.
Around the starting point we use a 20 meter radius to change the function automatically.

Function

- The copter is inside this 20 meter radius around the starting point
If you now activate the function [CareFree](#) the copter will set the "forward direction" in the direction where the red rigger (front) of the copter points. During the whole flight this direction is forward (no matter in which direction the copter turns).
- The copter is outside this 20 meter radius around the starting point
If you now activate the function [CareFree](#) the copter will set a "line" between the starting point and the position where the copter is (no matter in which direction the copter points). This "line" if forward/backward. During the whole flight this direction is forward/backward (no matter in which direction the copter turns).

Mehr Infos zur Funktion sind hier nachzulesen: [CareFree](#)

6 Mixer-SETUP

• Mixer-SETUP

 Load...

Depending on the design of your copter and the number of used motors the right mixer must be loaded.

The mixer will set the number of used motors and also the direction of rotation.

This mixers are already include the MikroKopter-Tool:

Quadro.mkm	Quadro-X.mkm	Hexa.mkm	Hexa2.mkm	Hexa-X.mkm
				
Okto.mkm	Okto2.mkm	Okto2b.mkm	Okto3.mkm	Okto-U.mkm
				