en/MK-Parameter/Configuration

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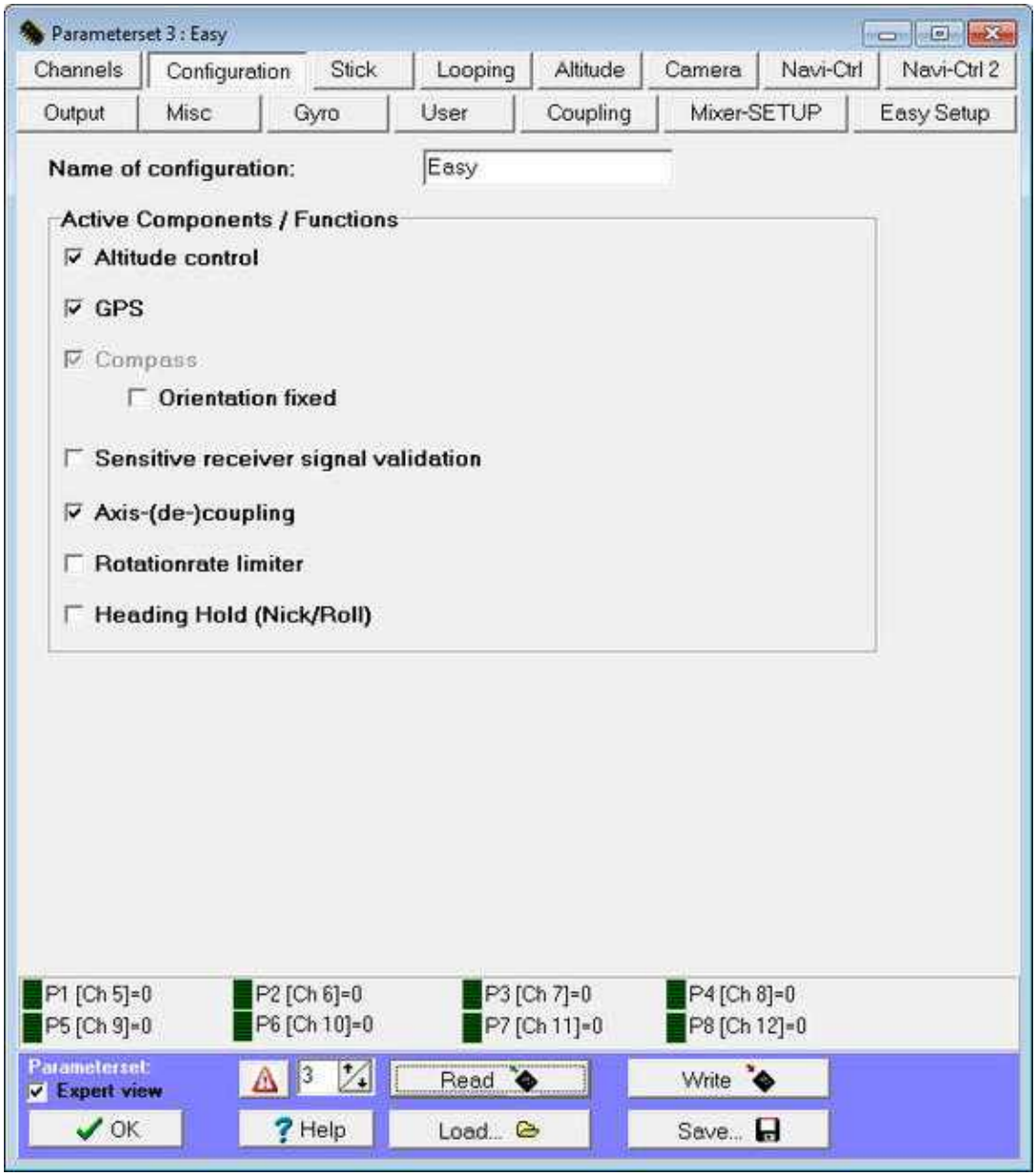
Quick selection
Open the description -> click Button

Channels	Configuration	Stick	Looping	Altitude
Camera	Navi-Ctrl	Navi-Ctrl 2	Output	Misc
Gyro	User	Coupling	Mixer-SETUP	Easy Setup

This page as an **PDF-Document**?
Click on that Symbol and wait a little moment... --->

Configuration

- deutsch


Parameterset 3 : Easy
Channels
Configuration
Stick
Looping
Altitude
Camera
Navi-Ctrl
Navi-Ctrl 2
Output
Misc
Gyro
User
Coupling
Mixer-SETUP
Easy Setup
Name of configuration:
Easy
Active Components / Functions
Altitude control
GPS
Compass
Orientation fixed
Sensitive receiver signal validation
Axis-(de-)coupling
Rotationrate limiter
Heading Hold (Nick/Roll)
P1 [Ch 5]=0
P2 [Ch 6]=0
P3 [Ch 7]=0
P4 [Ch 8]=0
P5 [Ch 9]=0
P6 [Ch 10]=0
P7 [Ch 11]=0
P8 [Ch 12]=0
Parameterset:
Expert view
3
Read
Write
OK
Help
Load...
Save...

In a total of five sets of parameters different settings can be stored in the Kopter. These can be accessed through the sticks after turning on the Kopter and the initialization.

- **Name of configuration**
  Each setting can be named under *Name of configuration* with a representative name. This is useful for example for different payloads, sporty flying or camera-flight etc.
  If a setting is completed or altered it must be saved under it's number in the MikroKoper with the function **WRITE**
  The MikroKopter acknowledged this with a appropriate number of short beeps.

  To select the settings with the transmitter the proceed as follows: :

  Setting 1 => Roll left + Nick middle **plus** Gas up + Gier left
  Setting 2 => Roll left + Nick up **plus** Gas up + Gier left
  Setting 3 => Roll middle + Nick up **plus** Gas up + Gier left
  Setting 4 => Roll right + Nick up **plus** Gas up + Gier left
  Setting 5 => Roll right + Nick middle **plus** Gas up + Gier left

- **Altitude control**
  Checked if the air pressure sensor on the FlightCtrl should be used.
- **GPS**
  In that case the GPS-System (NaviCtrl + MKGPS) is activated . Therefore GPS-functions like holding position (PositionHold), flying back to the start-point (ComingHome) and the fly-around with waypoints are possible.
- **Compass**
  Typically, this field is grayed out and active when GPS is selected.
  Only if there is no GPS-System on the copter and if you use e.g. a MK3Mag on your FlightCtrl you can deaktivate this and activate only "Compass". The single using of a MK3Mag is normally not customary.

    - **Orientation fixed**
      If this function is activated, the MikroKopter depends on the yaw and over again from the direction in which it has been at the start.
      Attention: If this function is enabled, the copter can not be completely turned!
- **Sensitive receiver signal validation**
  The *Sensitive receiver signal validation* was built specifically for the 35/40 MHz systems. A receiving failure is detected properly. If you use a 2.4GHz Transmitter / Receiver you did not need this function.
  (see also "Channels")
- **Axis-(de-)coupling**
  Here you can enable or disable the axis coupling. The axle coupling prevents the MikroKopter after a curve is flown to be loopsided.
  Function is active when the yaw angle will be corrected internally. This function should always be activated.
- **Rotationrate limiter**
  Additional limitation of the rate of rotation. With this option the characteristic of the gyro is lifted at the ends.
  This prevents rapid maneuver, which is regulated at a certain rate of rotation. Applies only to pitch and roll. (Only interesting for beginners).
- **Heading Hold (Nick/Roll)**
  In this mode and after a flight maneuver the MikroKopter is not automatically going back into a horizontal position when the stick is in neutral position. This setting, for example, are possible for most types of loops.
  This function is for experienced pilots! This one needs a lot of flying experience!
  -> ATTENTION: Who wants to fly HH the I-part must be increased to the proportion of the main controller (e.g. to 30)!

    - More information about flying with Heading Hold you can read here: HeadingHold (information only in german)