

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

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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 MikroKopter 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 deactivate 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)