

General Guide

Synerduino Ardu 2560

Multicopter

Latest Version - 2024

For more Information:
www.synerflight.com



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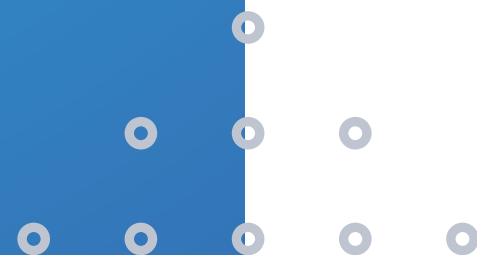
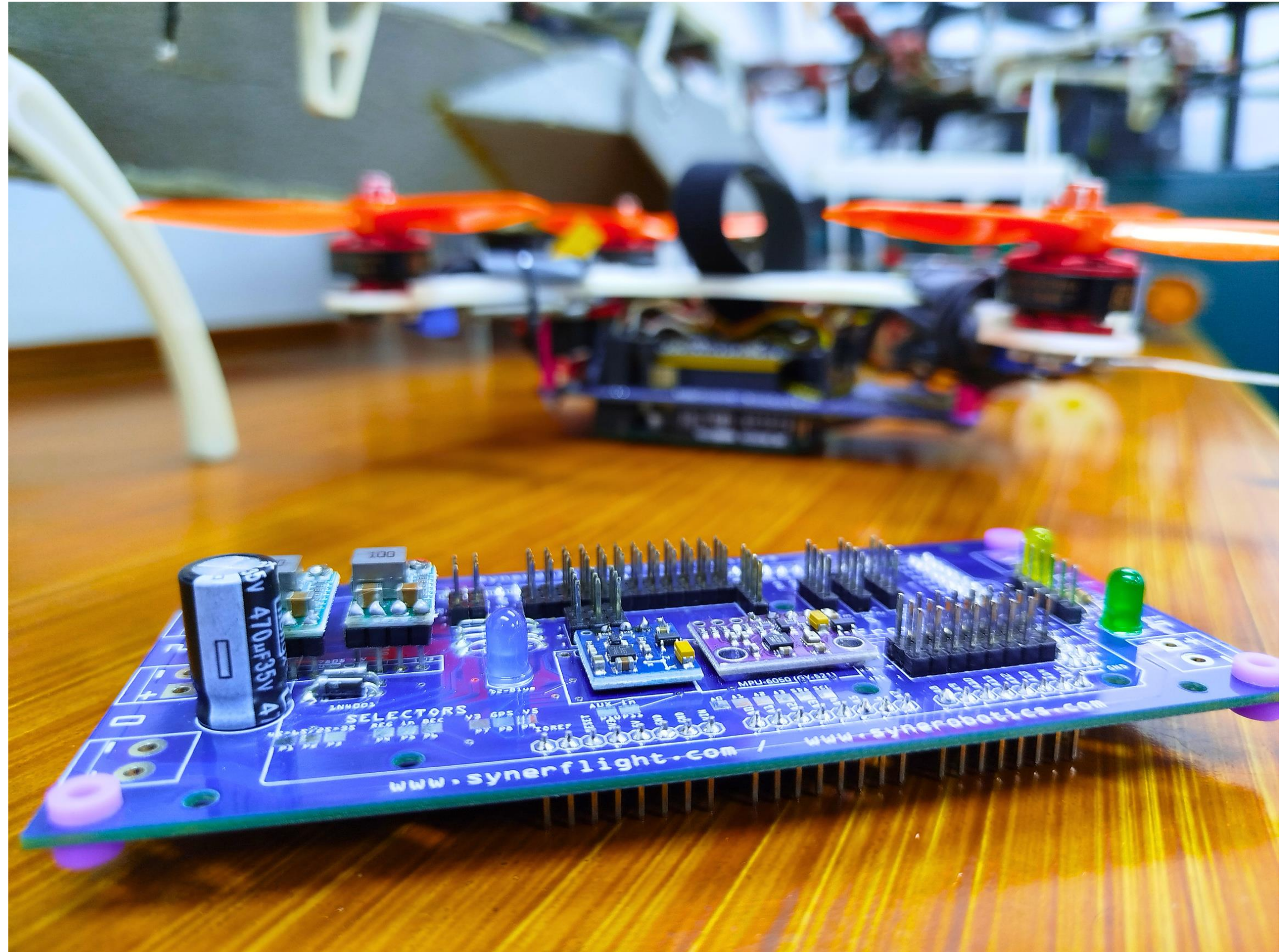
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INTRODUCTION

Synerduino Ardu 2560 brings back the classic feel of Arduino, reminiscent of the 2012-2014 era. With its compatibility with the iconic 2560 board and the Arduino IDE, configuring your projects through Sketch .ino files has never been more straightforward. Built on top of the widely used Arduino boards, Synerduino Ardu 2560 is designed with the academic environment in mind, making it a perfect choice for educational and hobbyist projects alike.



SYNERDUINO ARDU 2560

ABOUT THE BOARD



Power

- Input Voltage from Arduino Board: 3.3-5V
- PWM Power Rail Regulated – 5V at 1.5A
- Drone Power Input Voltage – 12.6V (3S) or 25.2V (6S)
- Power Distribution Lines – 80A

Properties

- Dimensions: 128 x 62 x 28 mm LWH / (V1.1)135mm x 62mm x 28mm
- Weight: 46.1g
- 4 Solder Pads for 4 ESCs and Motors
- 15 3-Pin Digital Headers
- 8 3-Pin Analog Headers
- 5 4-Pin Serial Headers

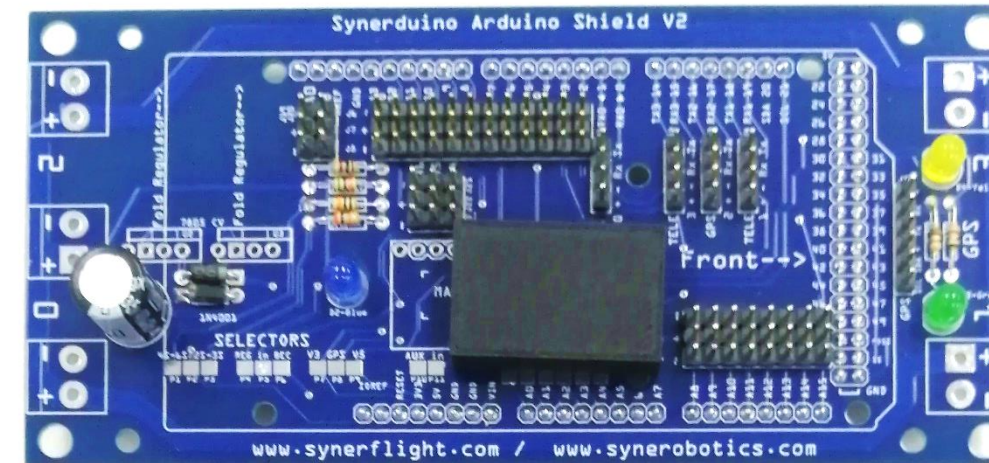
Sensors

- Gyroscope + Accelerometer: MPU6050
- Magnetometer: QMC5883 / HMC5883
- Barometer: BMP280

BOARD VERSIONS

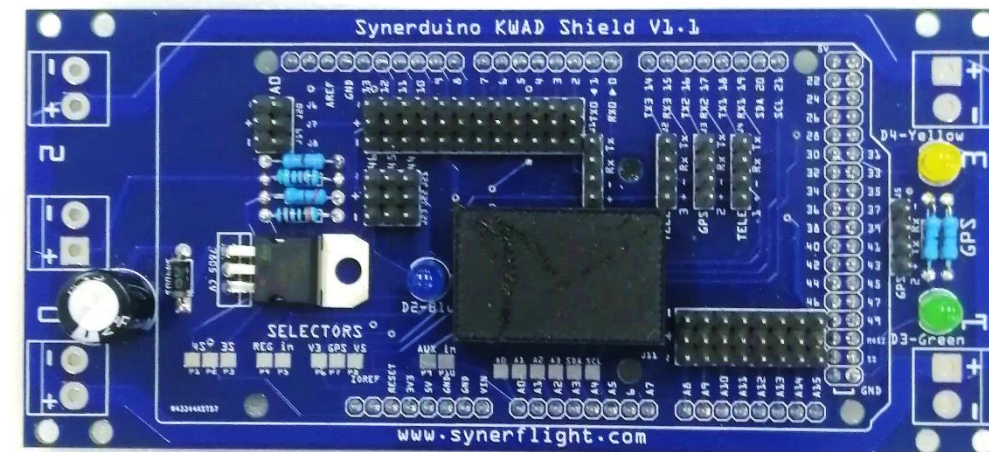
Synerduino Arduino Shield V2 -2024

- MPU9250
- QMC5883
- BMP 280



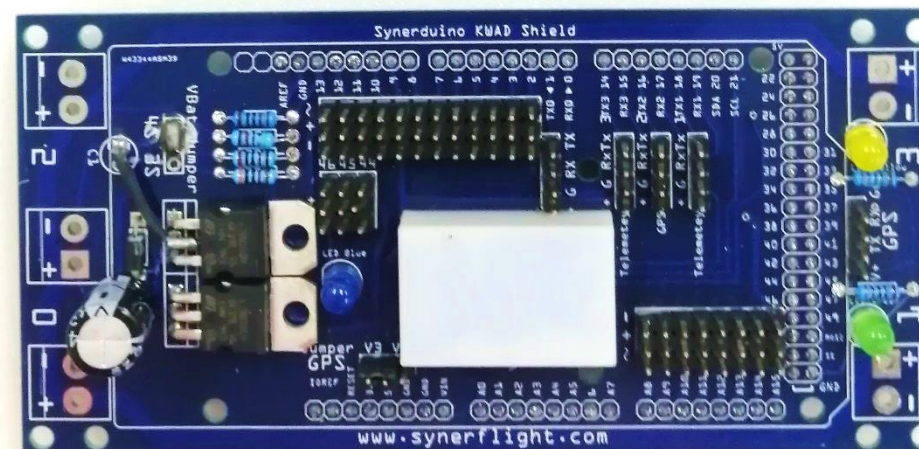
Synerduino Kwad Shield V1 -2021

- MPU9250
- MAG 9250
- BMP 180



Synerduino Kwad Shield Beta -2020

- L3G4200D
- ADXL345
- BMP 180
- MMC5883



PIN LAYOUT

Aux ADC in

Description: Auxiliary input for connecting additional sensors or components that output analog signals, allowing the board to read and process external analog data.

Note: Input Voltage: 3.3-5V

Power Input

Description: This is the main power input for the board, designed for a 3-cell (3S) - 4-cell (4S) LiPo battery - 11.1V and 14.8V respectively. It powers the ESCs, servos, and other components on the board.

Soldering Note: ESCs should only be soldered on the top side of the board, ensuring the solder joints do not penetrate through to the bottom.

Jumper Pads Selector Zone

Description: These are PWM (Pulse Width Modulation) output pins used to control the motors through ESCs (Electronic Speed Controllers) or servos.

ESC / Servo PWM Out

Description: These are 36 PWM (Pulse Width Modulation) output pins used to control the motors through ESCs (Electronic Speed Controllers) or servos.

Serial Pins

Description: These are 12 serial pins for communication with external devices or modules like GPS or telemetry systems using a UART interface.

GPS Serial Pins

Description: These are 6 dedicated pins for connecting a GPS module's TX and RX (Transmit and Receive) lines for serial communication.

GPS LED

Description: This LED blinks or stays lit depending on whether the GPS is locked (has found satellites) or is searching for a signal.

Status LED

Description: A general-purpose status indicator for the board. It could be used to indicate power, initialization, or operational status.

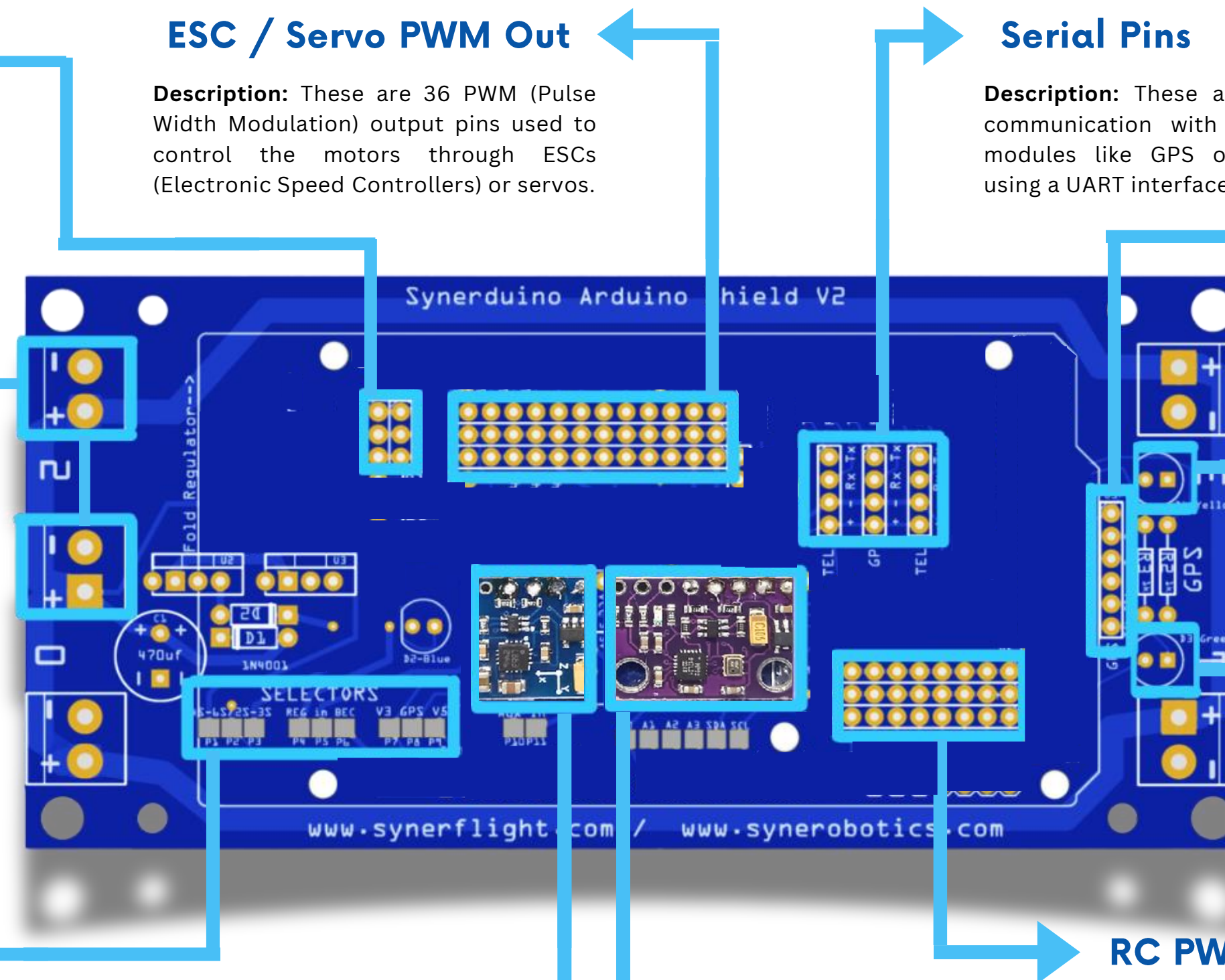
RC PWM In

Description: These are 24 pins which accept PWM signals from an RC (radio control) receiver, allowing manual control via an RC transmitter.

5883 Mag

Note: These modules may vary depending on the manufacturer or version. Some versions might use different sensor combinations that could exclude certain components, like the magnetometer.

IMU MPU-9250



KEY FEATURES OF THE BOARD

Power Terminals (+ and -)

These terminals supply the voltage needed for the entire drone system, ensuring that the right amount of power is distributed across the board and connected components.

Capacitor

Ensures that power distributed to pins and components remains stable, reducing the risk of erratic behavior during flight due to power fluctuations.

GPIO and I/O Headers

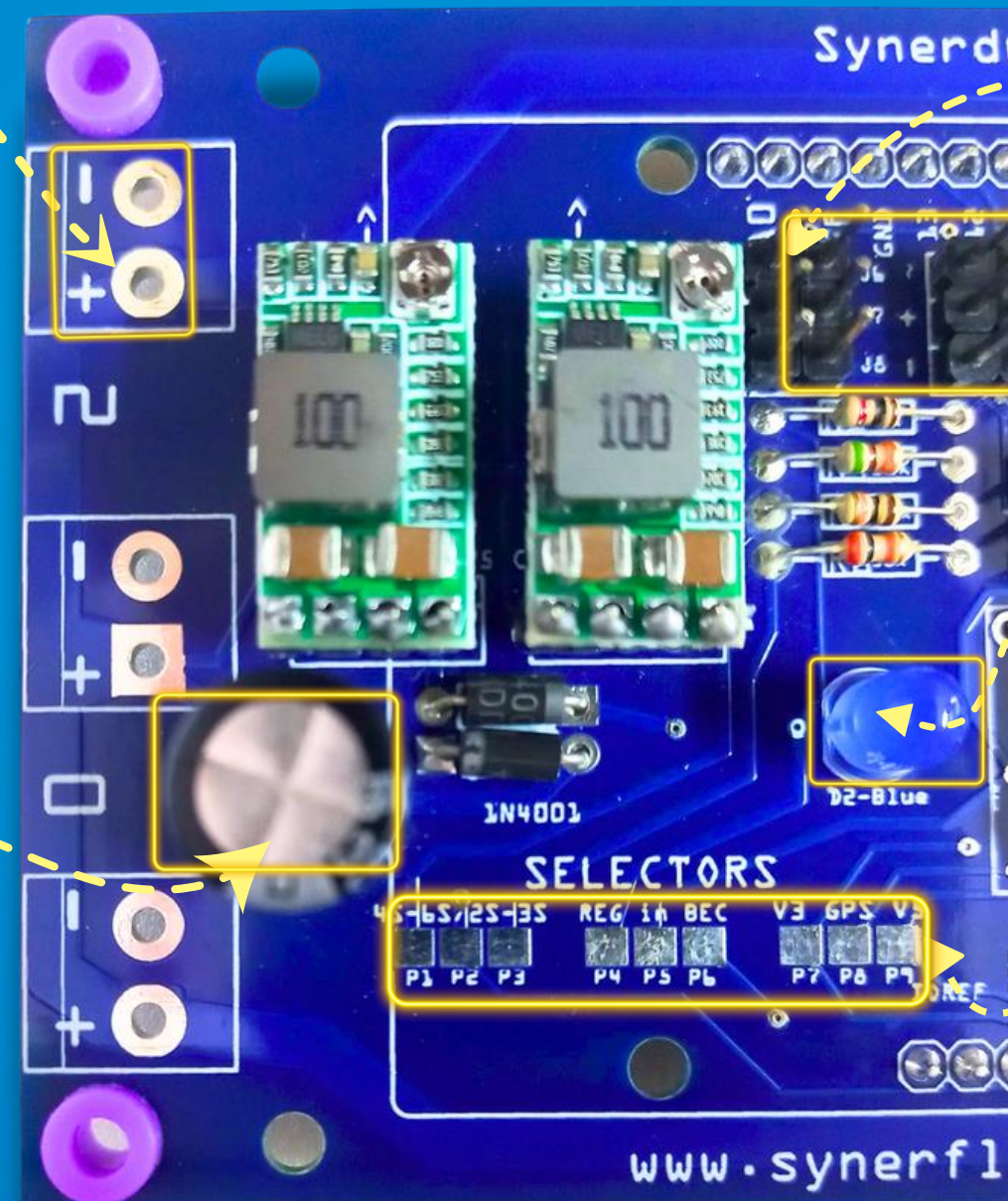
Each pin corresponds to a specific function, such as reading throttle, aileron, elevator, and rudder signals from the receiver, processing sensor data, or controlling motors, making them critical for the drone's operation.

LED Indicator

Provides a quick visual confirmation that the board and connected pins are functioning correctly, which is particularly useful during pre-flight checks.

Selector Pins

Selector pins customize the board's power management, allowing you to configure ESCs, GPS modules, and sensors according to flight needs.



SYNERDUINO KIT COMPONENTS

Synerduino Kit + 250mm Frame

Description: A ready-made frame and controller kit for building a small quadcopter. The frame size (250mm) is suitable for small to mid-size drones.

Main Controller Board

Description: This is the central flight controller, responsible for processing inputs from sensors.

Plastic Casing

Description: High-current connector for connecting the battery.

Bluetooth and GPS Module

Description: Bluetooth module for wireless communication and GPS for positional tracking and navigation.

XT60 Plug

Description: High-current connector for connecting the battery.

Washers and Dampeners

Description: Washers spread out the load to keep screws tight, while dampeners absorb shocks and reduce vibrations.

Propellers (5x4.5 or 5x4)

Description: These are 5-inch blades in both clockwise and counterclockwise rotations, essential for balancing and stabilizing the quadcopter.

Spacers

Description: These are 5-inch blades in both clockwise and counterclockwise rotations, essential for balancing and stabilizing the quadcopter.

2300kV Motors

Description: High-speed motors delivering up to 1000g thrust each.

ESCs

Description: Motor controllers, some with BEC for powering extra components, running on 3S-4S batteries.

Servo Wires

Description: Cables for connecting servos or components to the flight controller.

SYNERDUINO KIT COMPONENTS



**WHAT'S
NEW?**

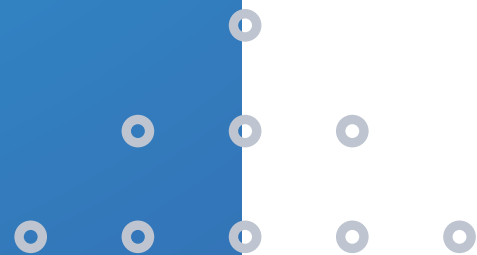
Features:

- Compatible with MultiWii (open source RC multi rotor flying platform)
- Compatible with Arduino Mega 2560 and Uno
- Ground Station with Flywii GUI or Synerflight App
- IMU 10DOF
- Supports 3S/4S Batteries
- 4 Output ESC Pads
- Mode Selection Pads (V1.1)
- ADC sensor input (V1.1)
- Highly customizable

Technical Specifications:

- Physical Dimensions: 128 x 62 x 28 mm LWH
- Weight: 46.1g
- 4 Solder Pads for 4 ESCs and Motors
- 15 3-Pin Digital Headers
- 8 3-Pin Analog Headers
- 5 4-Pin Serial Headers

ASSEMBLY



TOOLS AND MATERIALS



PLIERS

Used for gripping, bending, and cutting wires or components during the assembly process.



TAPES

Electrical and double-sided tapes used for securing wires and insulating electrical connections.



SOLDERING SET

Essential for soldering components and making secure connections between wires and circuit boards.



HEX DRIVER SET

Utilized for tightening or loosening hex screws commonly found in drone frames and components.



CUTTER

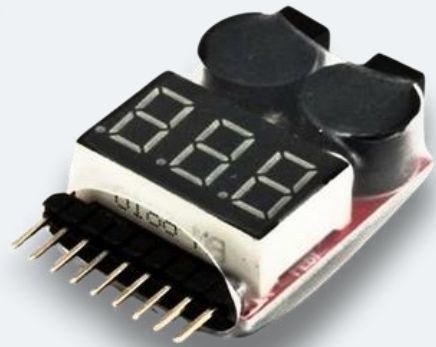
Handy for cutting zip ties, wires, or other materials to the desired length during assembly.



ZIP TIES

Used for bundling and securing wires, ensuring neat and organized cabling inside the drone.

TOOLS AND MATERIALS



BATTERY ALARM CHECKER

Monitors battery voltage, providing warnings when the battery is low to prevent damage or crashes.



LI-PO BATTERY CHARGER

Safely recharges Li-Po batteries, ensuring optimal battery health and longevity.



PVC GLUE

Used for assembling or reinforcing non-electrical parts of the drone frame and components.

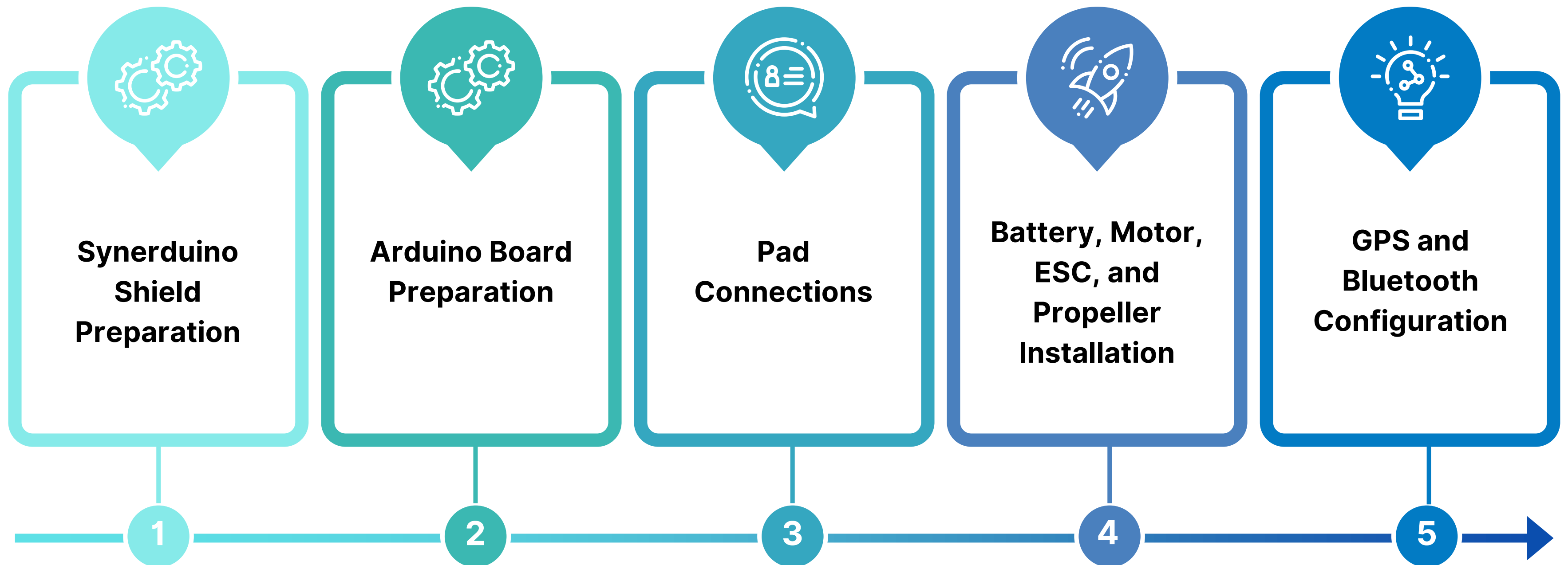


THREAD LOCKER PURPLE

Secures screws and fasteners in place, preventing them from loosening due to vibration during flight.

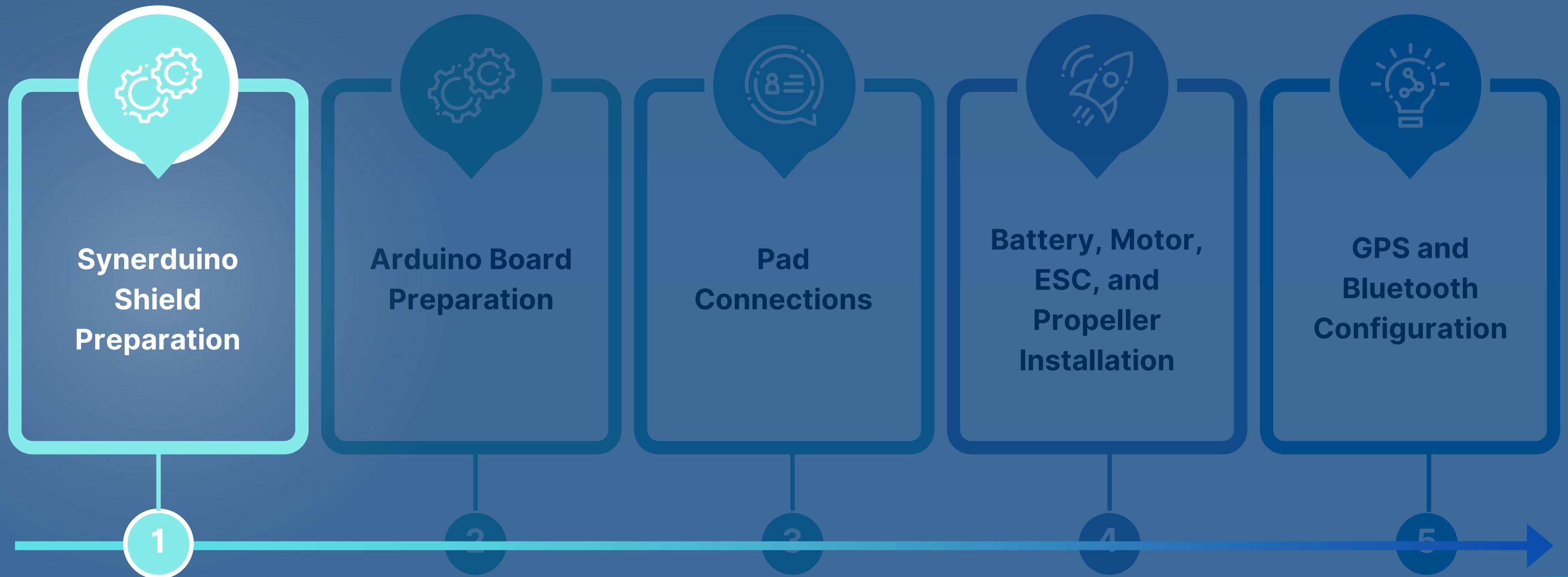
ASSEMBLING PROCESS

This section outlines the essential steps for assembling your Synerduino Drone Kit. Begin by gathering the necessary tools and materials, then prepare the Synerduino shield and the Arduino board. Finally, install the motor, Electronic Speed Controller (ESC), and propeller. Follow these steps carefully to ensure a successful assembly and get your drone ready for flight!

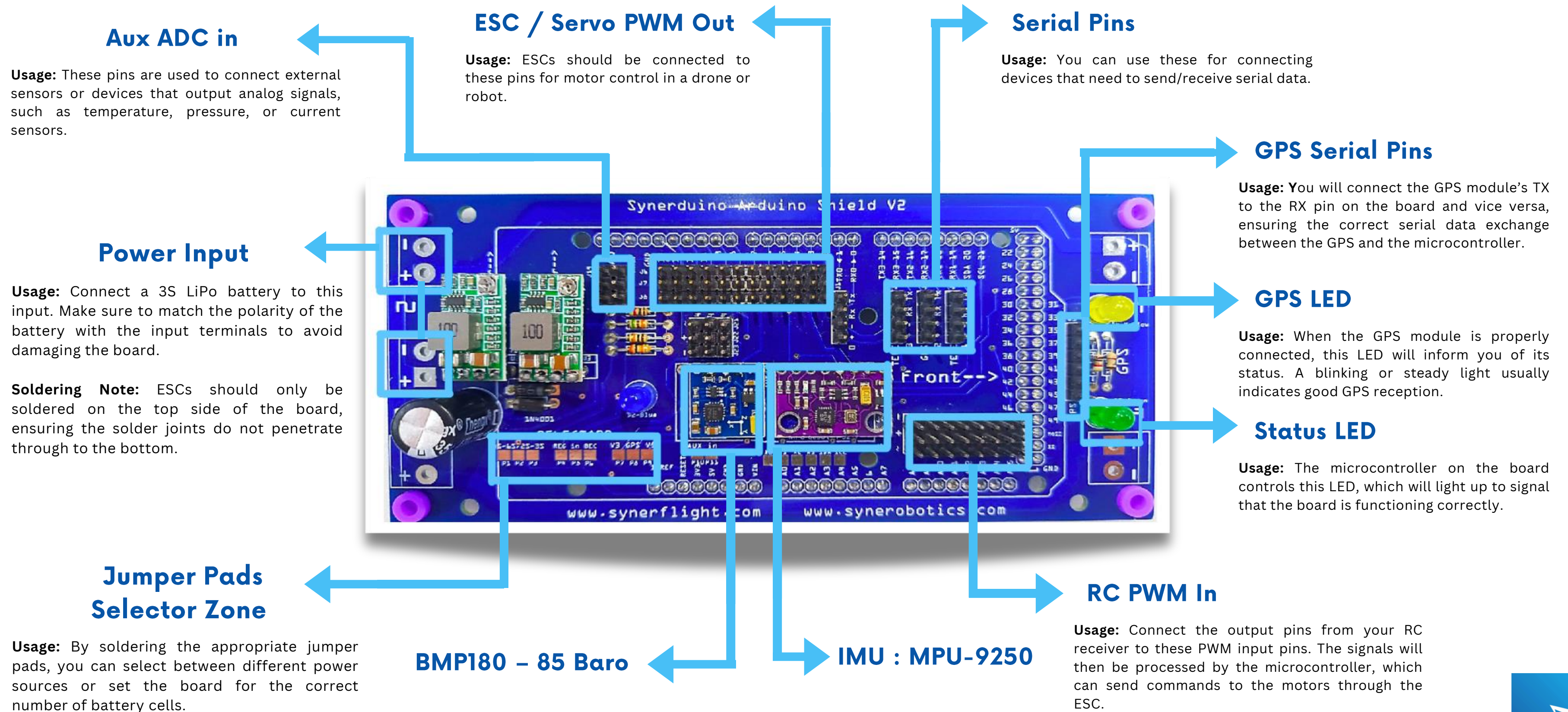


ASSEMBLING PROCESS

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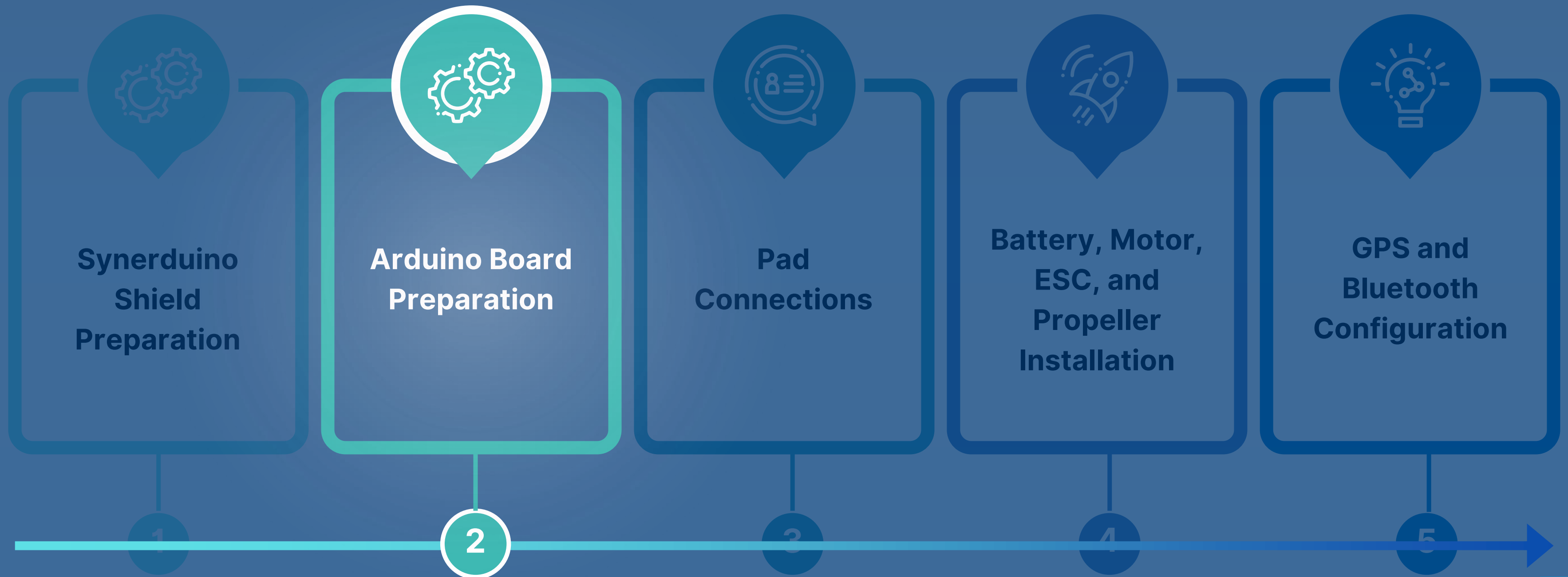


SYNERDUINO BOARD PREPARATION



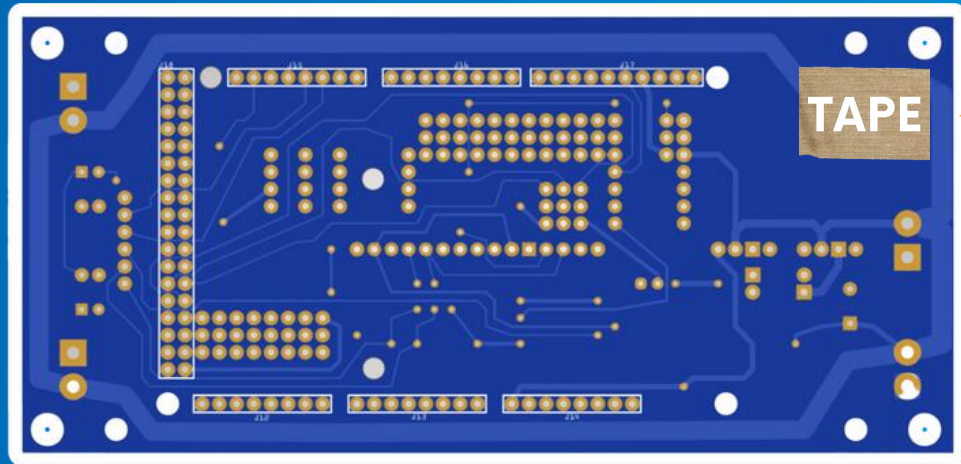
ASSEMBLING PROCESS

This section outlines the essential steps for assembling your Synerduino Drone Kit. Follow these steps carefully to ensure a successful assembly and get your drone ready for flight!



BOARD PREPARATION

Step 1: Add tape to these areas to ensure insulation from the Arduino board.



Add tape to the top right side corner at the back of the Synerduino board.

2560 MEGA



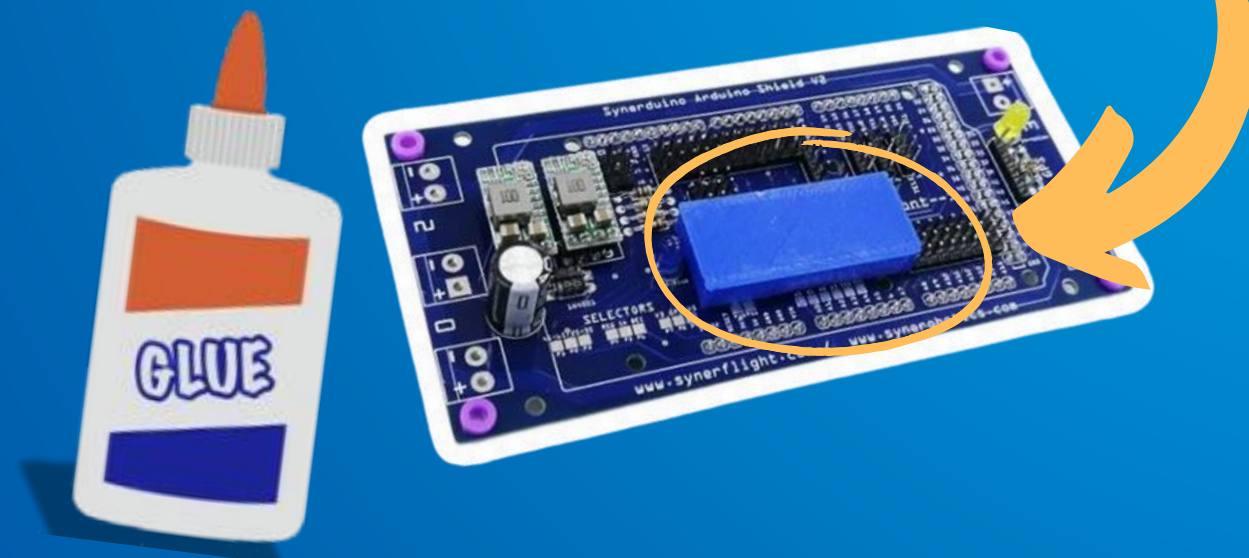
UNO 328



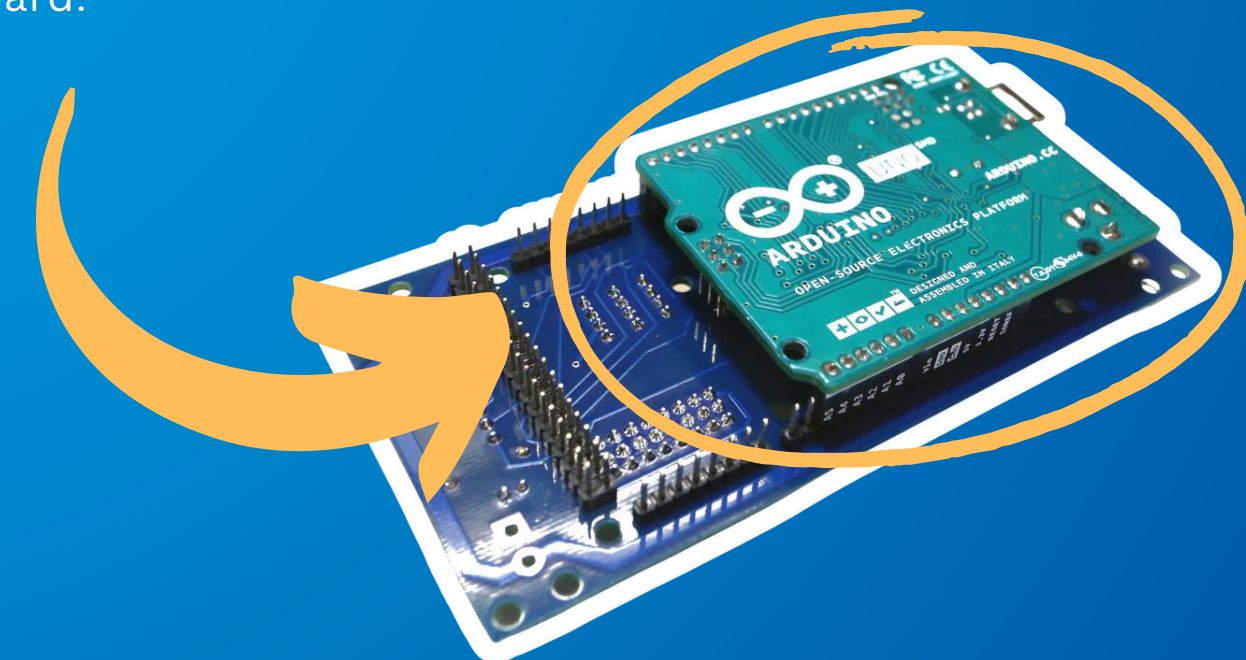
Add tape to the top-left side of the Arduino 2560 MEGA/UNO 328 board to cover the metal part.

Note: The exposed metal areas may come into contact with the Synerduino kit components, potentially causing a short circuit.

Step 2: Make sure to seal the cover onto the sensor using PVA glue, and allow it to fully dry before proceeding.

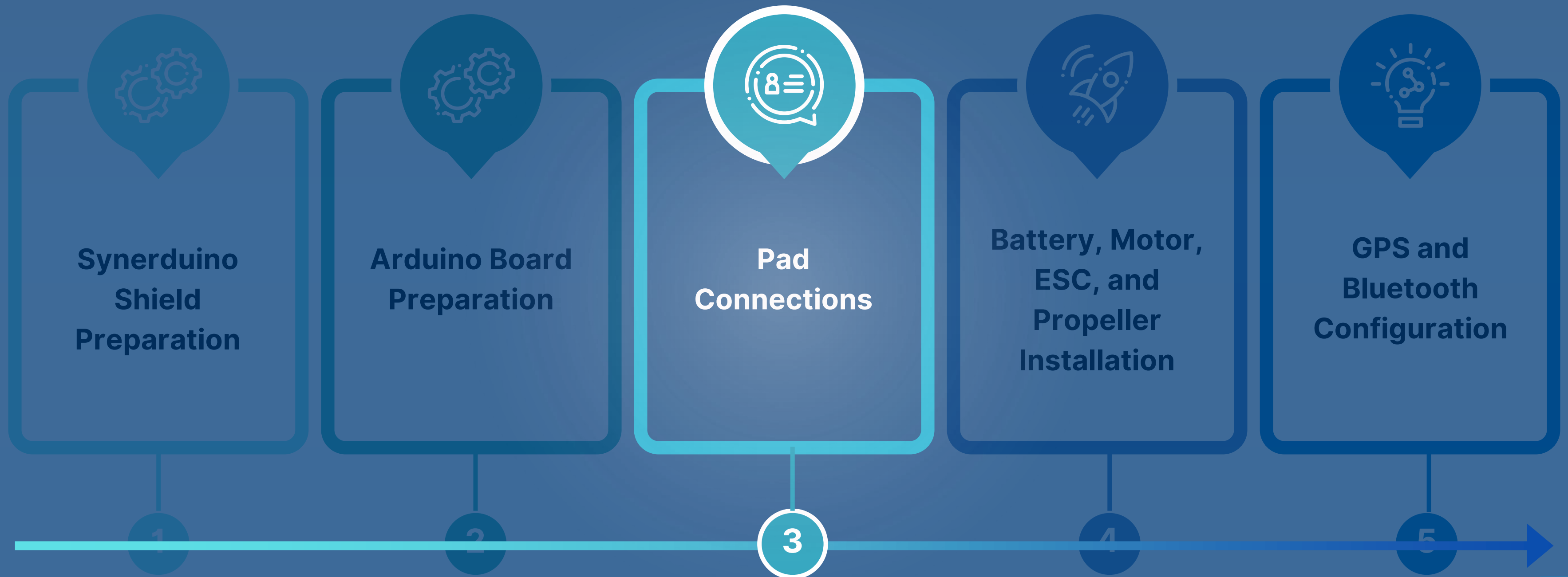


Step 3: Now, connect the Arduino Uno Shield to the back of the Synerduino board.



ASSEMBLING PROCESS

This section outlines the essential steps for assembling your Synerduino Drone Kit. Follow these steps carefully to ensure a successful assembly and get your drone ready for flight!



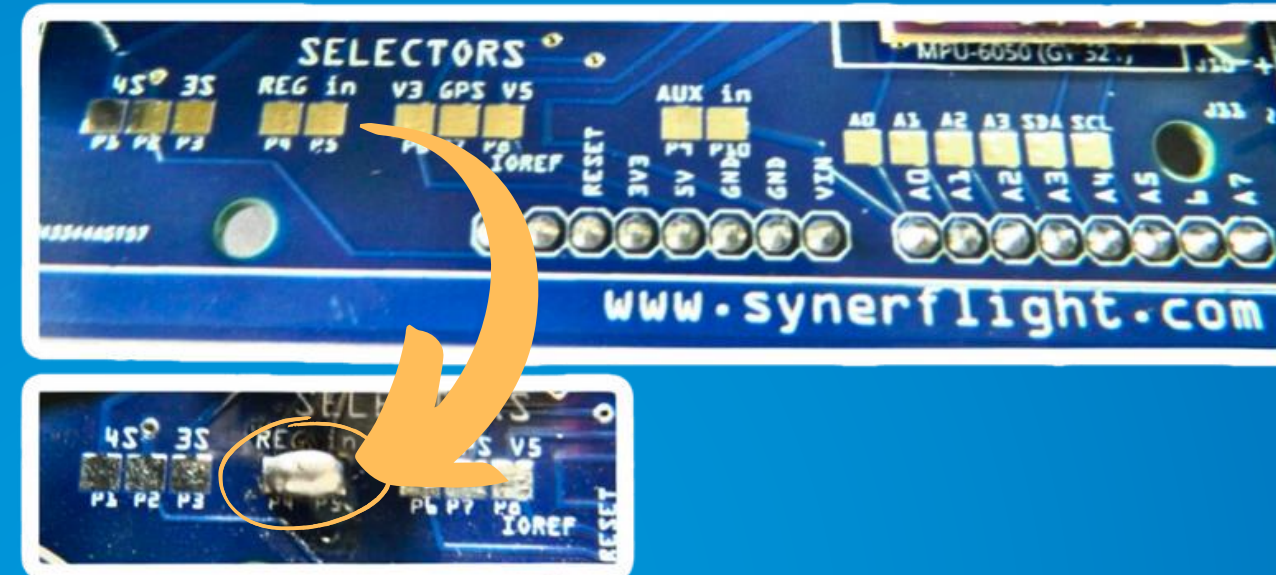
PAD CONNECTIONS

SYNERDUINO KWAD SHIELD V1 BOARD

Step 4: Power Selector Jumper Pads are directly added to the main board, enabling users to choose the desired power source through a simple soldering step:

Apply a **small blob of solder** to bridge the specific pads corresponding to your preferred power option.

This approach provides a secure connection, giving you the flexibility to configure power supply without additional components, all in a compact and reliable manner.



Battery cell monitoring 4s or 3s

To use the onboard battery monitoring with Aux In:

- Set to 3S if you're using a 1S-3S battery.
- Set to 4S if you're using a 4S battery.
- Leave it open when using Aux In as external sensors or when using 5S-6S batteries.

5V Regulator from battery

- For Reg In, short the pads to use the regulator to power both the Synerduino and Arduino board, along with the built-in power distributor.

GPS Pins V+ voltage in front of the board

The 2nd GPS pin comes with a voltage selector:

- Set to 5V for a regular GPS.
- Set to 3V for an external I2C sensor, such as a magnetometer.

Analog 0 pin Auxin / Battery monitor

For Aux In:

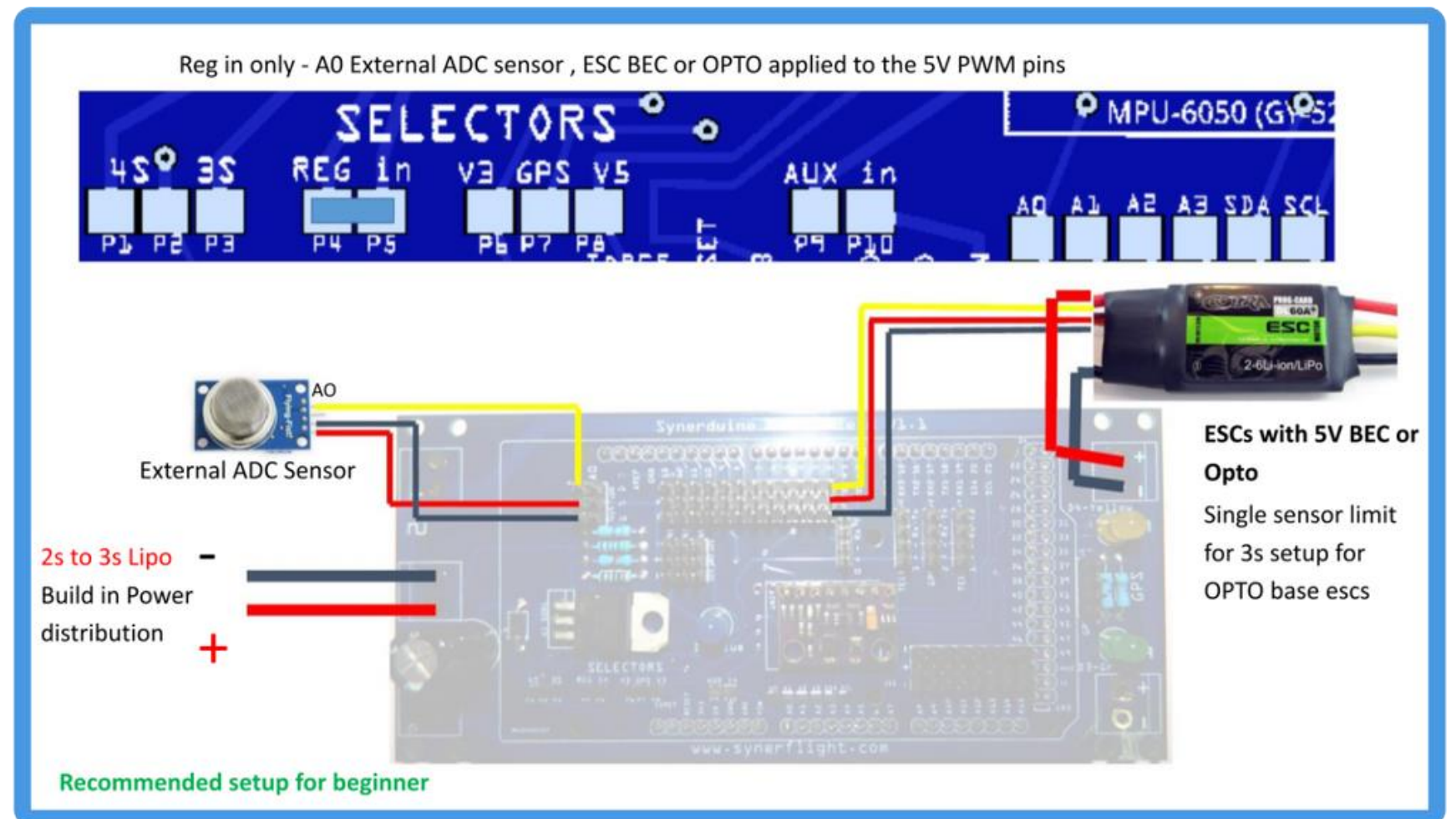
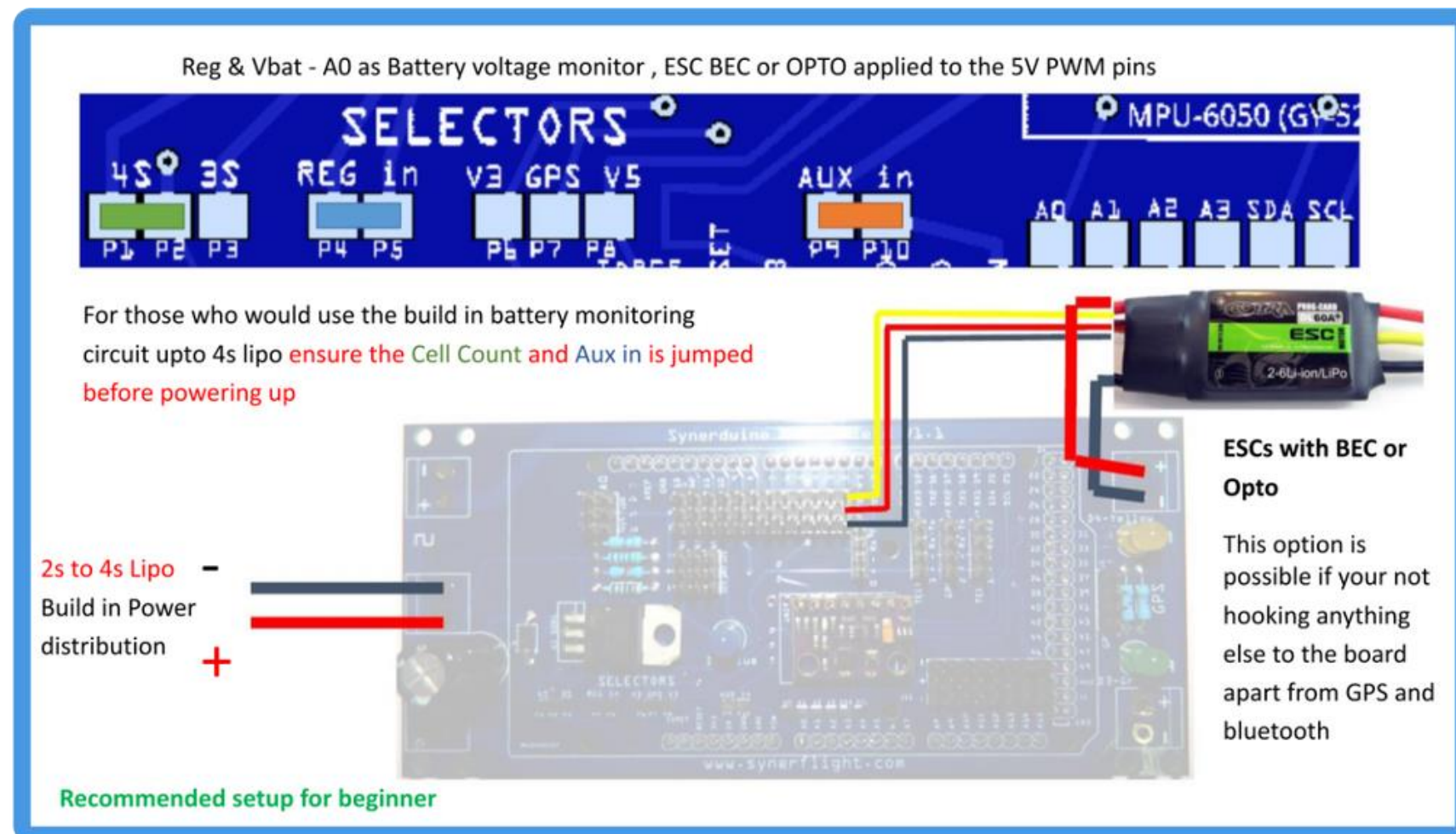
- Leave it open to utilize the A0 pins for external ADC sensors.
- Short the pads to use the built-in battery monitoring. Ensure the Cell Selector is set to 3S or 4S, depending on the battery configuration.

External i2C A4 and A4

For External Sensors not supported by the Board

PAD CONNECTIONS

SYNERDUINO KWAD SHIELD V1 BOARD



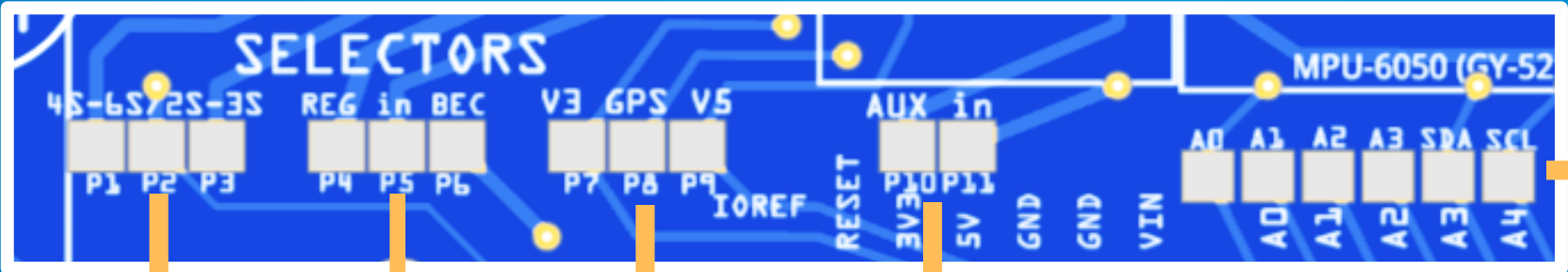
PAD CONNECTIONS

SYNERDUINO ARDUINO V2 BOARD

Step 4: Power Selector Jumper Pads are directly added to the main board, enabling users to choose the desired power source through a simple soldering step:

Apply a **small blob of solder** to bridge the specific pads corresponding to your preferred power option.

This approach provides a secure connection, giving you the flexibility to configure power supply without additional components, all in a compact and reliable manner.



Battery cell monitoring 4s or 3s

To use the onboard battery monitoring with Aux In:

- Set to 3S if you're using a 1S-3S battery.
- Set to 4S if you're using a 4S battery.
- Leave it open when using Aux In as external sensors or when using 5S-6S batteries.

5V Regulator from battery

- For Reg In, short the pads to use the regulator to power both the Synerduino and Arduino board, along with the built-in power distributor.
- Bec to Used ESC's BeC to power the Synerduino shield and Arduino Board

GPS Pins V+ voltage in front of the board

The 2nd GPS pin comes with a voltage selector:

- Set to 5V for a regular GPS.
- Set to 3V for an external I2C sensor, such as a magnetometer.

External i2C A4 and A4

For External Sensors not supported by the Board

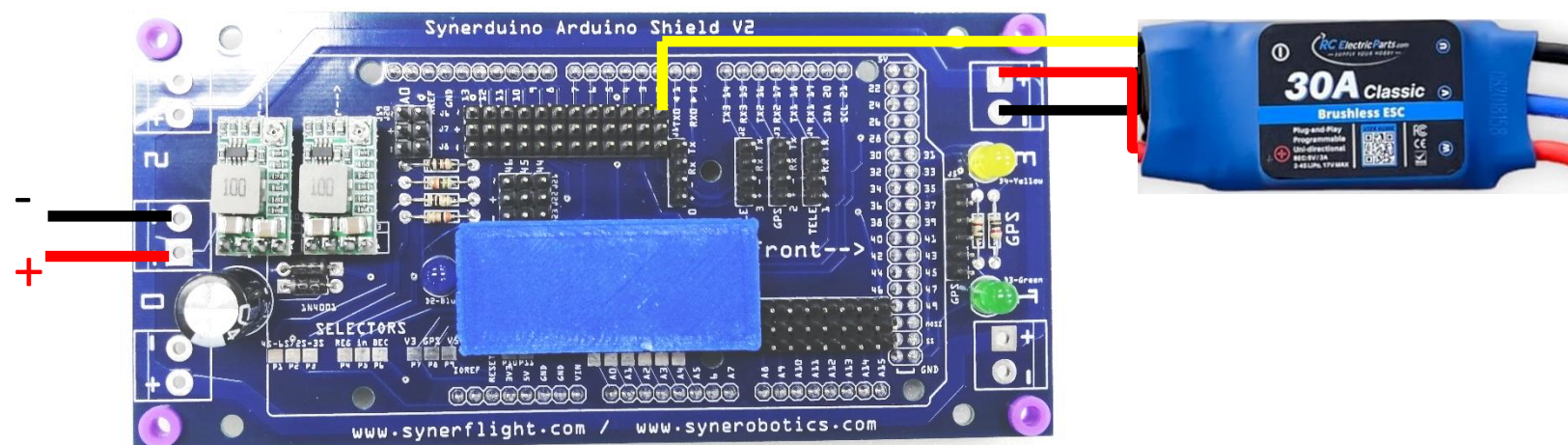
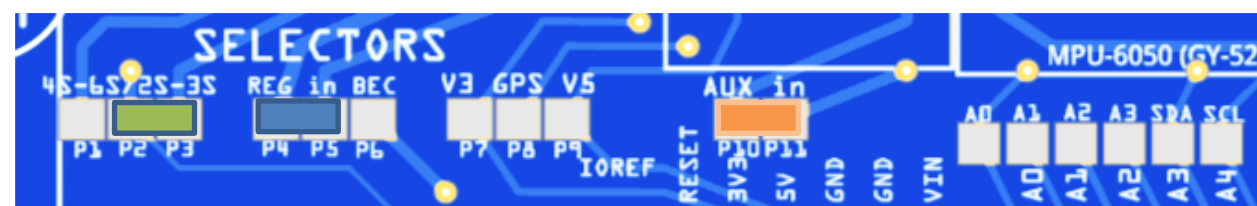
Analog 0 pin Auxin / Battery monitor

For Aux In:

- Leave it open to utilize the A0 pins for external ADC sensors.
- Short the pads to use the built-in battery monitoring. Ensure the Cell Selector is set to 3S or 4S, depending on the battery configuration.

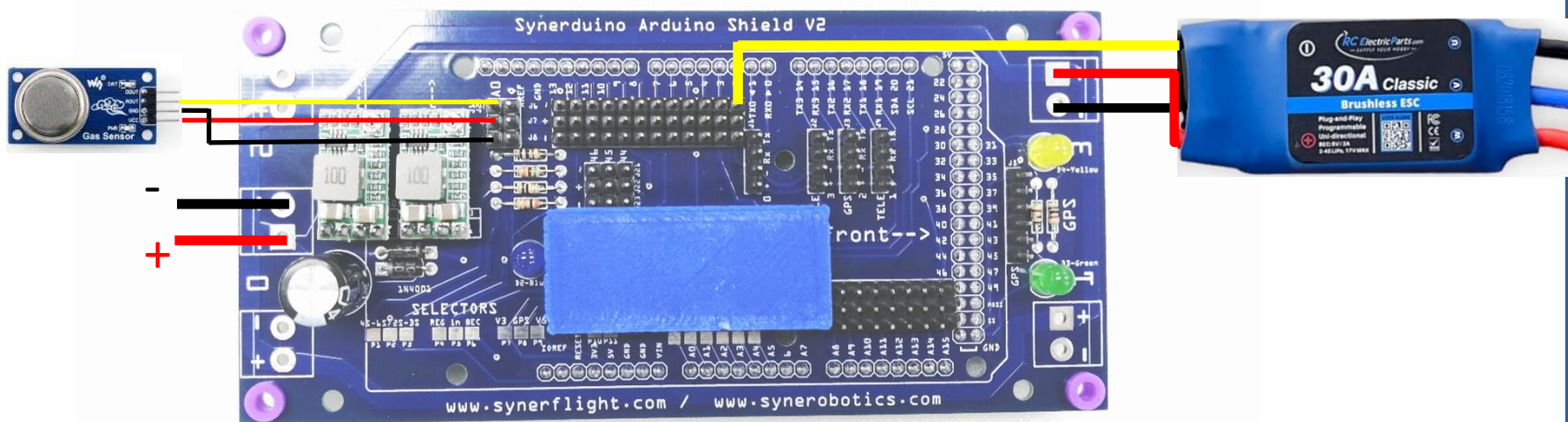
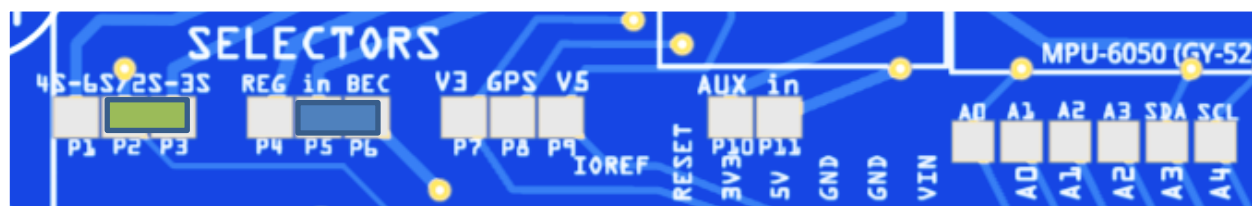
PAD CONNECTIONS

SYNERDUINO ARDUINO SHIELD V2 BOARD



Reg in – to use the onboard power supply to run the board up to 3A

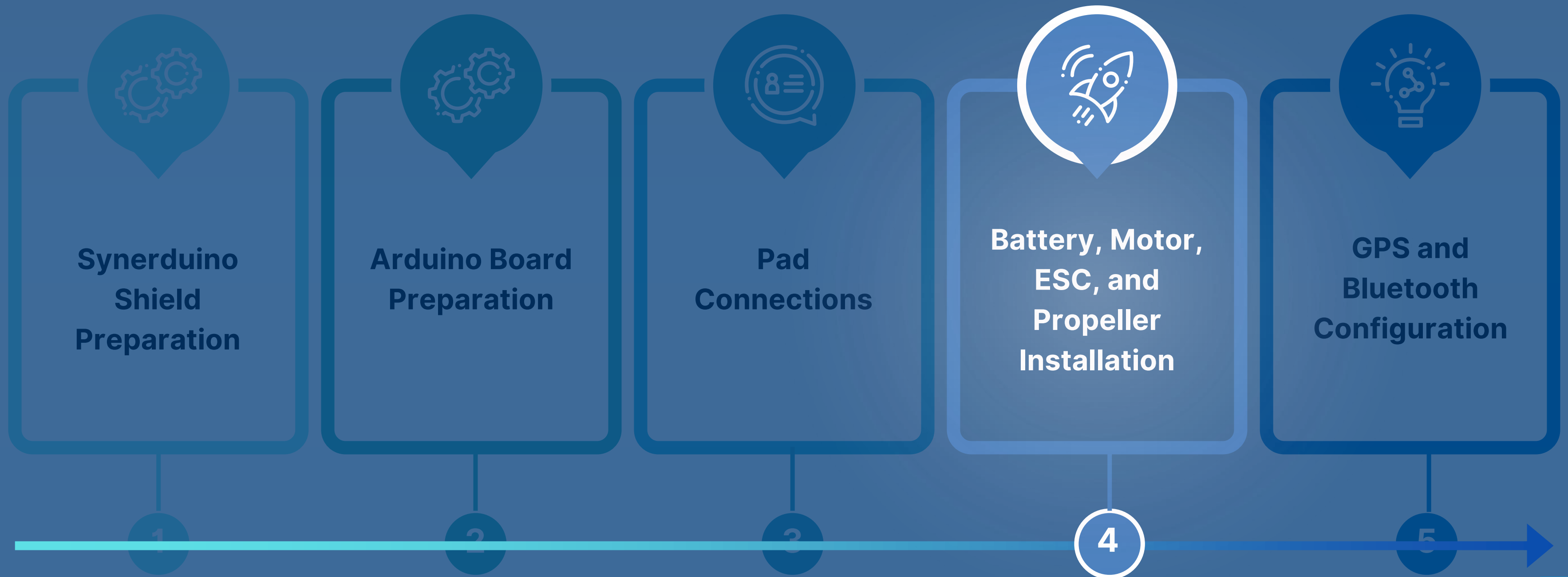
Aux in – to Read the Battert Voltage assign by the 4s-6s or 2s-3s pads



BEC in – if your using External BEC or ESC Bec to provide much needed Power to run Servos and External sensors and Companion Hardware

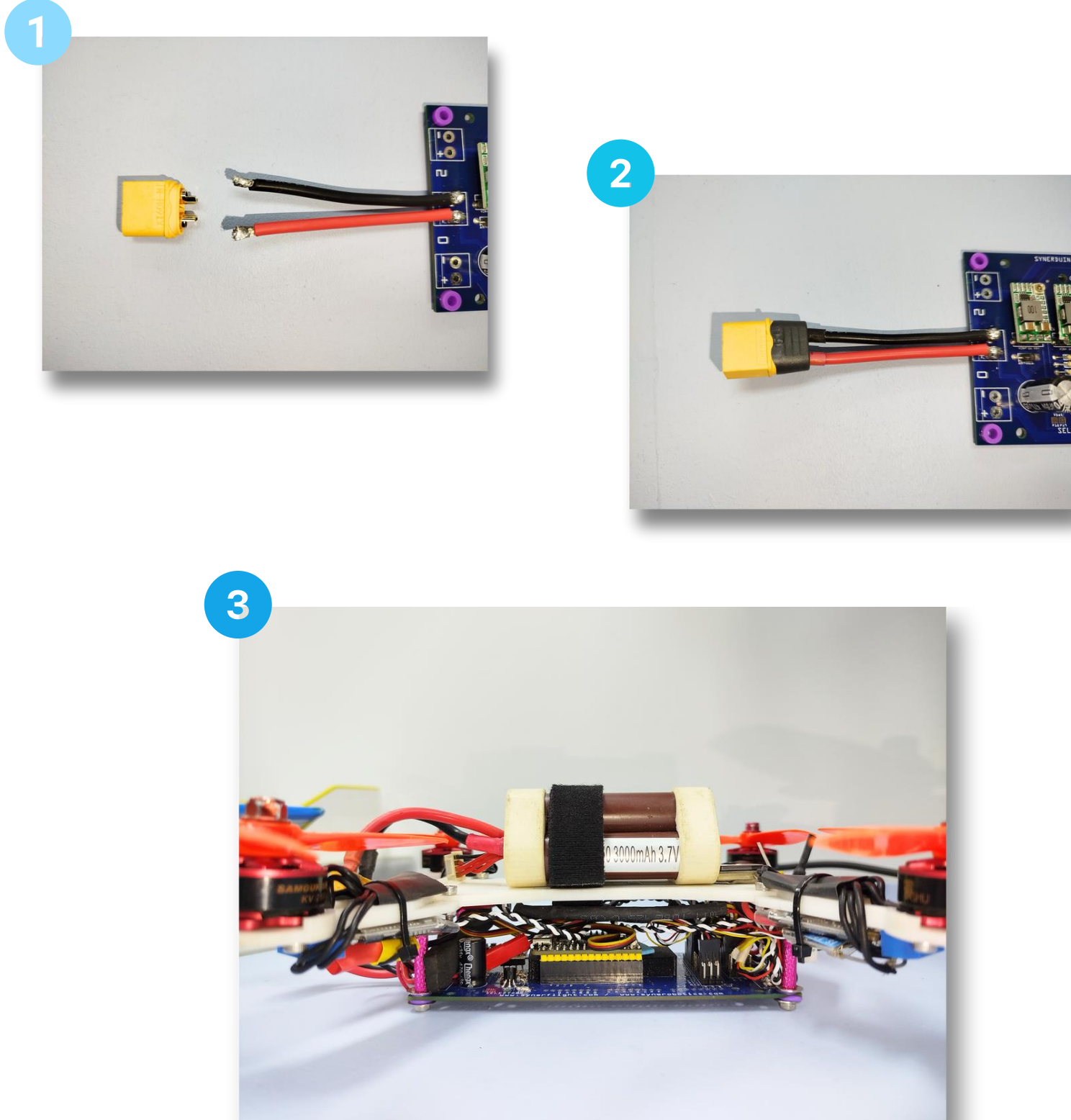
ASSEMBLING PROCESS

This section outlines the essential steps for assembling your Synerduino Drone Kit. Follow these steps carefully to ensure a successful assembly and get your drone ready for flight!



BATTERY INSTALLATION

STEPS



- 1 Connect the battery cable to the power connector.
- 2 Secure the connection to prevent detachment.
- 3 Secure the battery using straps or clips to prevent movement during operation.

NOTE: Always check battery voltage before installation to ensure it's fully charged.

MOTOR INSTALLATION

STEPS

1



2



1

Prepare the motor along with the two screws and nuts. Threadlock with PVA glue or purple thread locker

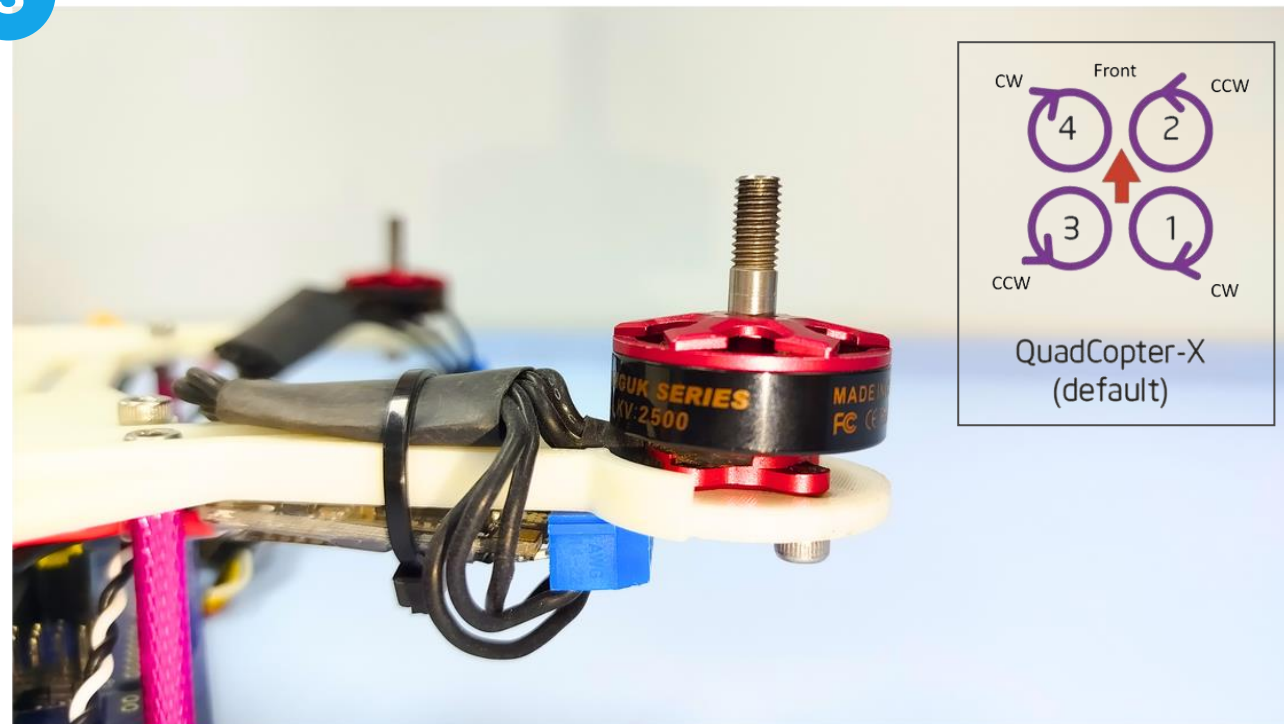
2

Secure the motor onto the designated motor mount, ensuring it aligns with the screw holes.

3

Connect the motor wires (usually three) to the ESC (Electronic Speed Controller), ensuring proper pairing (color-coded or numbered).

3

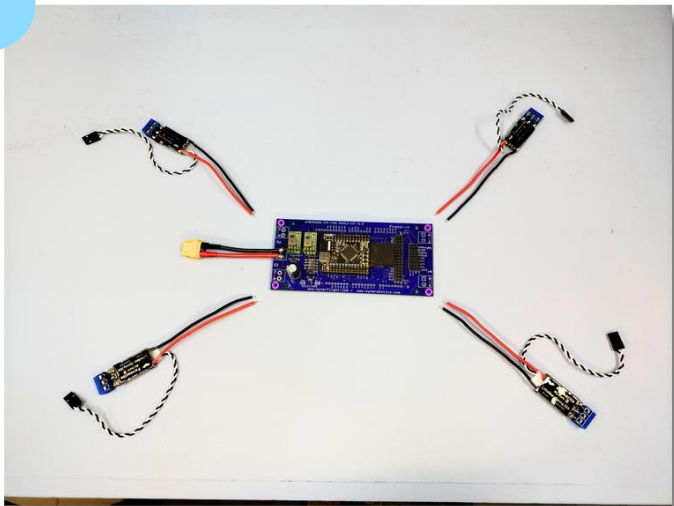


NOTE: If your motor has directional markings, ensure proper orientation for correct propeller spin.

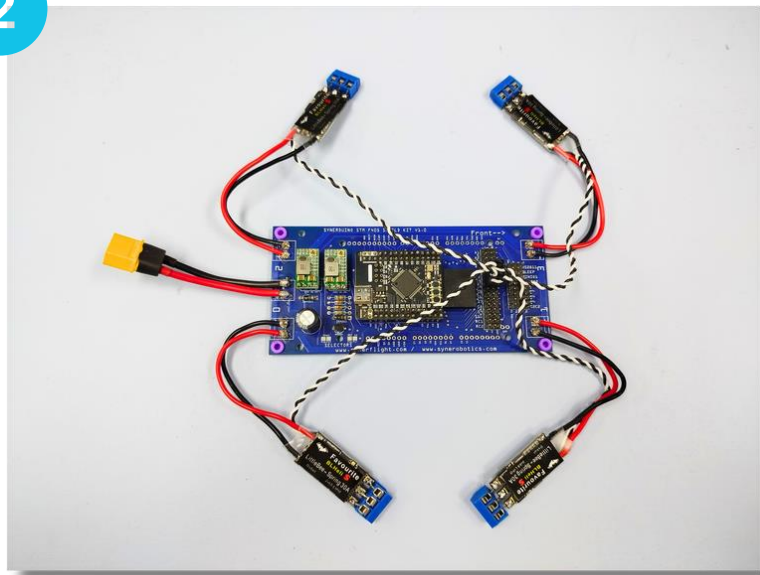
ESC INSTALLATION

STEPS

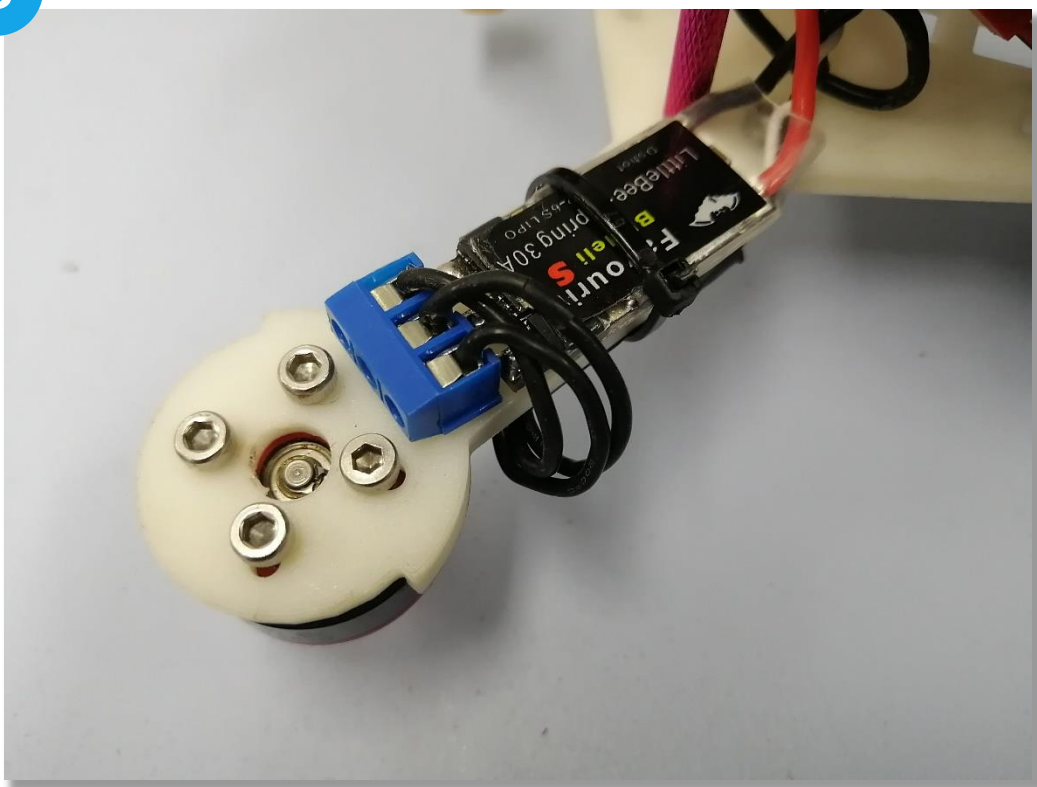
1



2



3



1

Properly arrange the ESC modules and wiring layout.

2

Connect the ESCs to the Synerduino board, ensuring wires are correctly positioned and soldered.

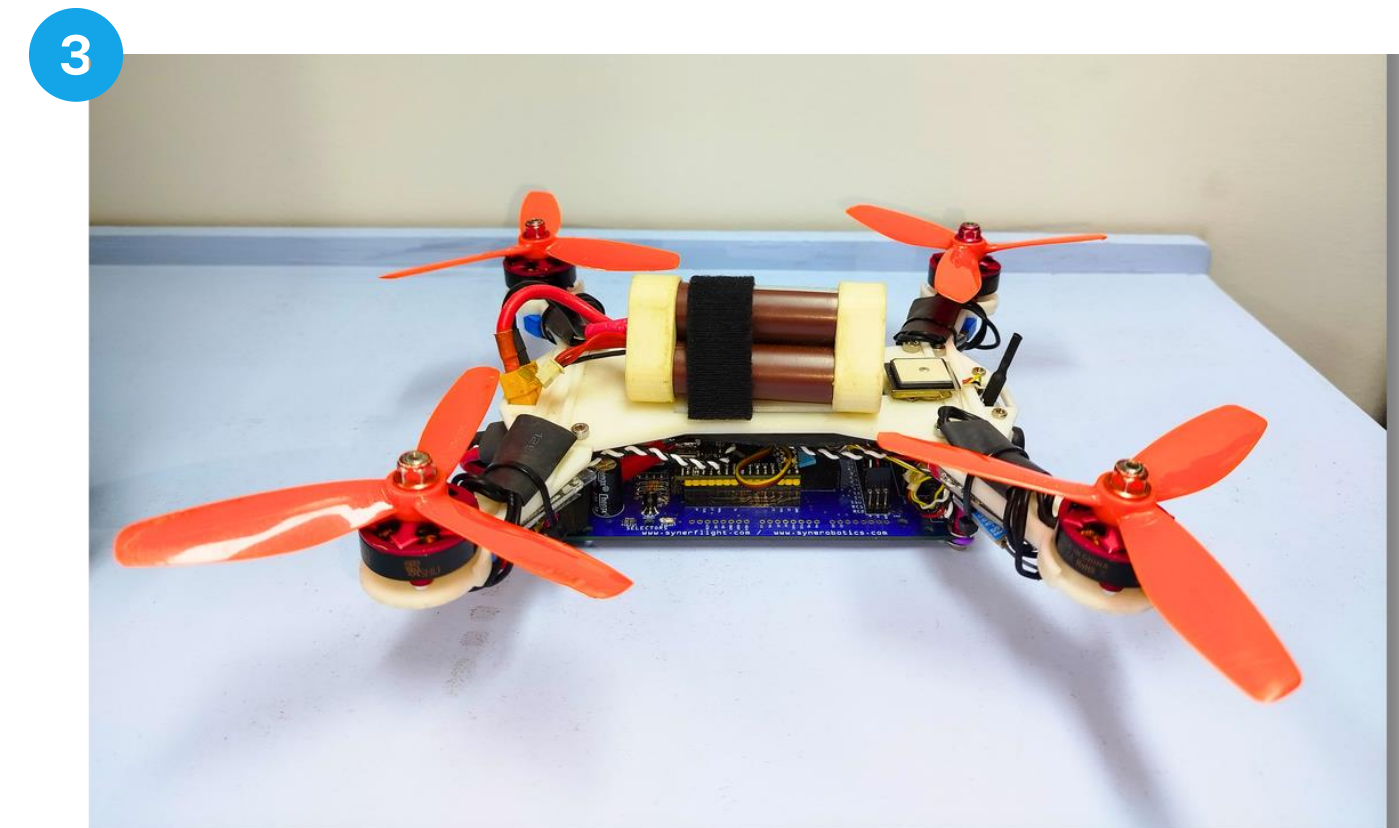
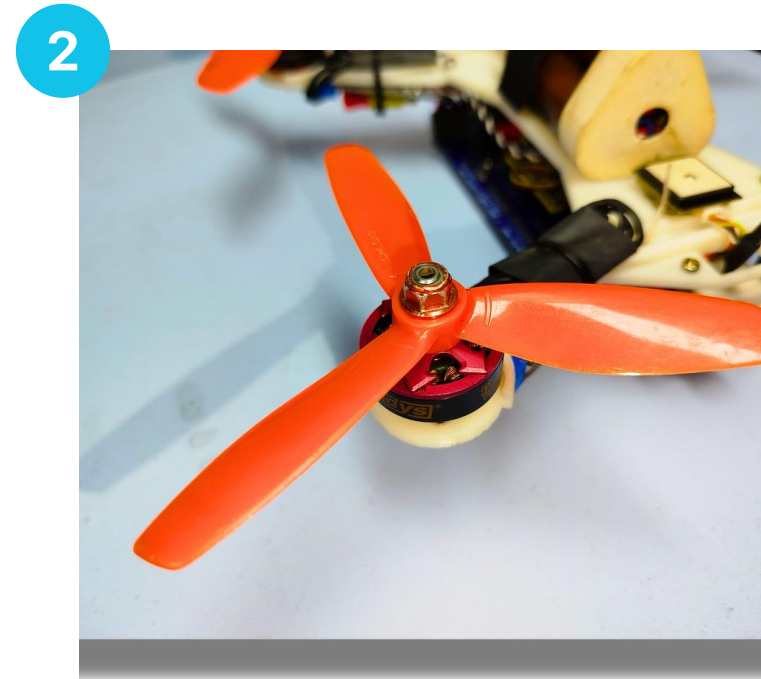
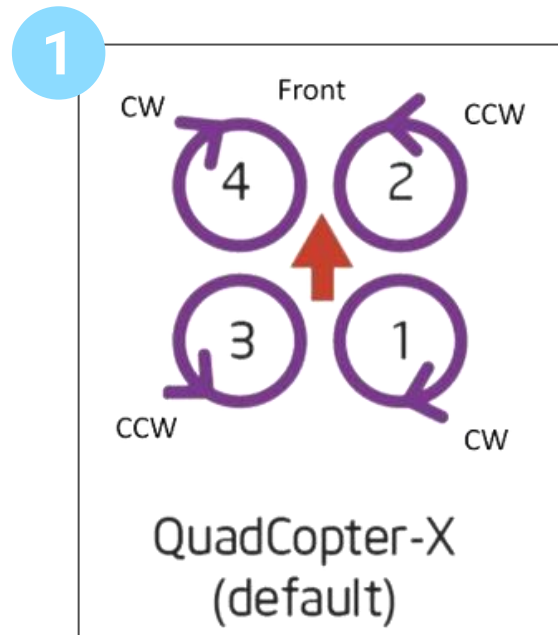
3

Ensure that the ESC modules are securely zip-tied to the drone chassis and placed near the motor.

NOTE: Program the ESC to suit your motor's specifications if required.

PROPELLER INSTALLATION

STEPS



1

Match the correct propeller to the motor, ensuring you have clockwise (CW) and counterclockwise (CCW) propellers in the right positions.

2

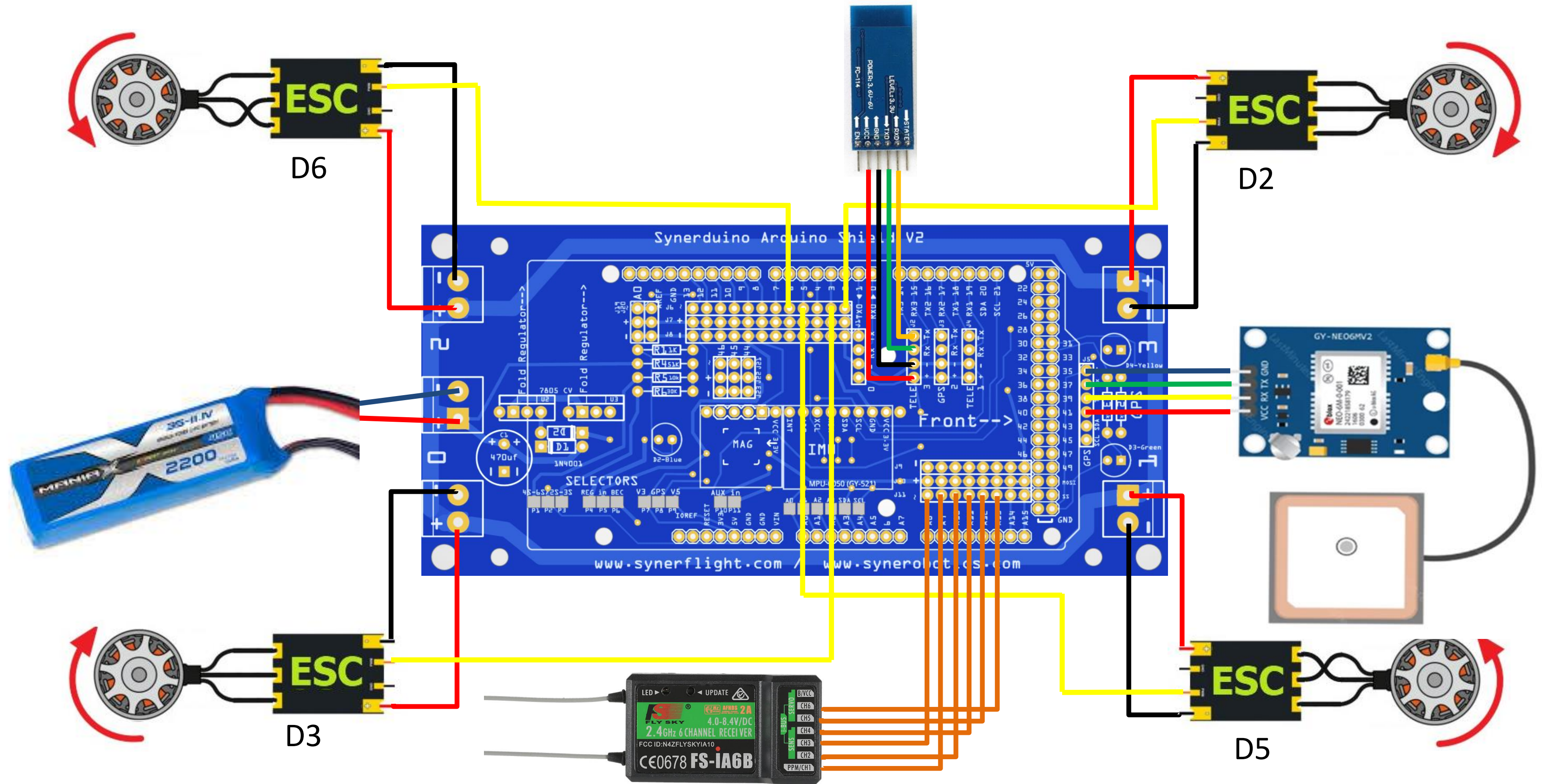
Push the propeller onto the motor shaft and tighten it with the provided nut or locking mechanism.

3

Repeat the steps on the other sides, and ensure that the propellers are firmly secured.

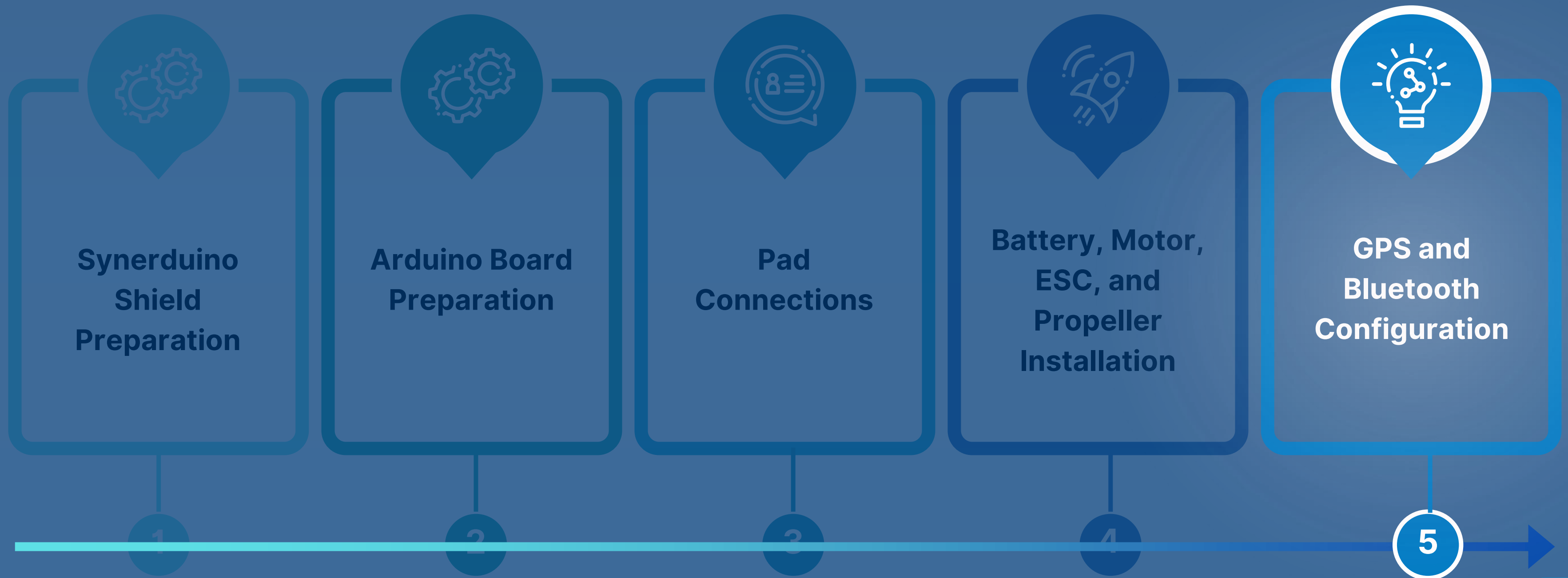
NOTE: Ensure no obstruction in the propeller's path for smooth rotation.

BATTERY, MOTOR, ESC, & PROPELLER INSTALLATION



ASSEMBLING PROCESS

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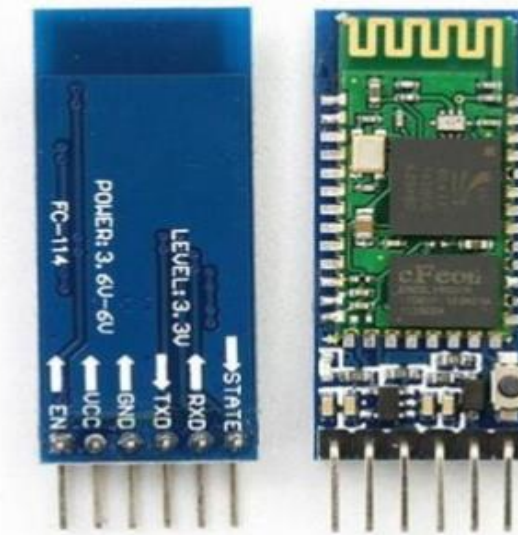
TELEMETRY



38400 OR 57600 FOR SIK RADIO
DEPENDENT IF USES 433MHZ OR
900MHZ (63kbps)



38400 FOR XBEE RADIO



115200 FOR BLUETOOTH HC-05

STANDARD FOR ALL DRONES TO USE SERIAL LINK AS TELEMETRY MAINLY ON YOUR TX RX SERIAL PORTS , NOTE: THE LOWER THE FREQUENCY OF THE RADIO THE LOWER THE BAUD IS NEEDED ,

MOST DRONES REQUIRE MINIMUM 63kbps AIRSPEED TO COMMUNICATE PROPERLY
PROTOCOL IS MSP RAW OR MAVLINK

BLUETOOTH CONFIGURATION

TO CONNECT THE **BLUETOOTH HC-05 MODULE** TO THE BOARD, ENSURE THE HEADERS ARE ARRANGED CORRECTLY. FOLLOW THIS WIRING CONFIGURATION:

VCC (Bluetooth) connects to **+** (Board)

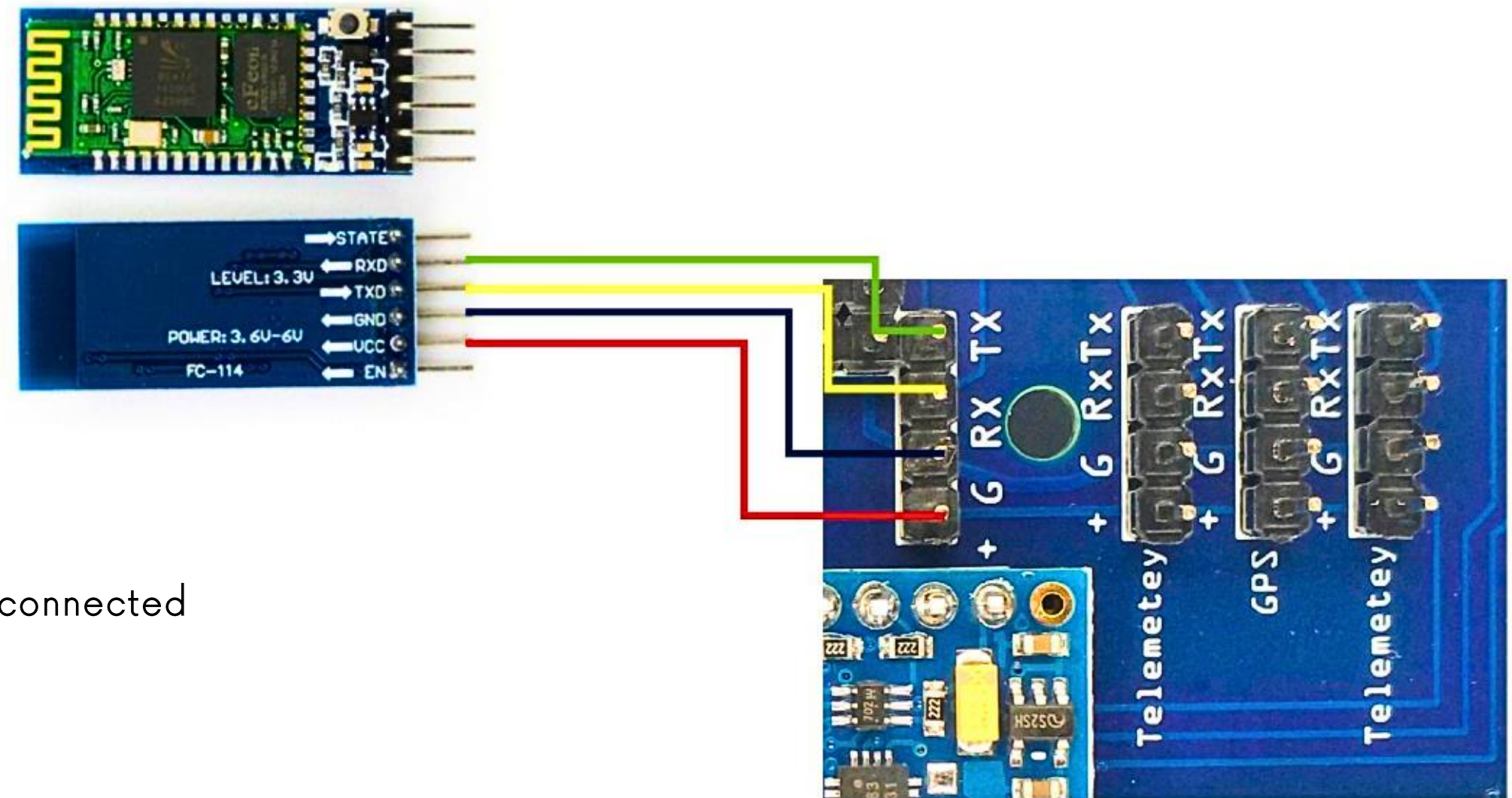
GND (Bluetooth) connects to **G** (Board)

TX (Bluetooth) connects to **RX** (Board)

RX (Bluetooth) connects to **TX** (Board)

Any Serial Radio can be configured to run on Serial 0, 1, or Serial 3. with the matching Baud

Serial 0 can be used for telemetry only if the USB is disconnected

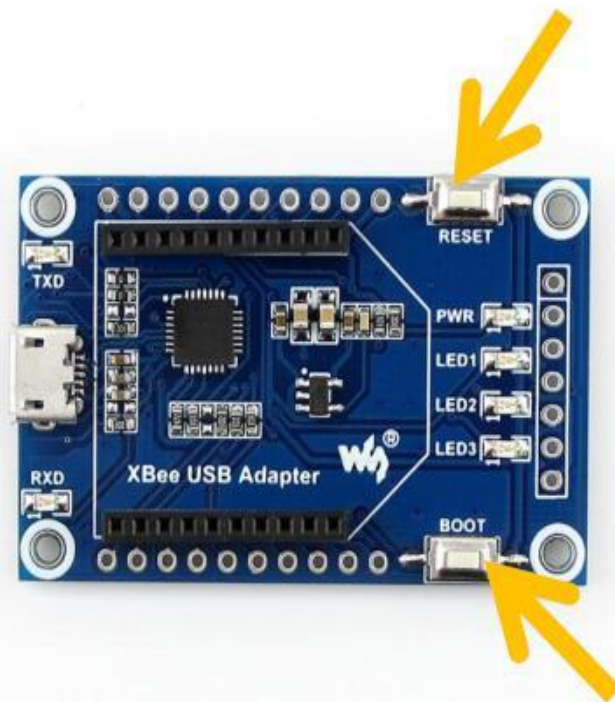
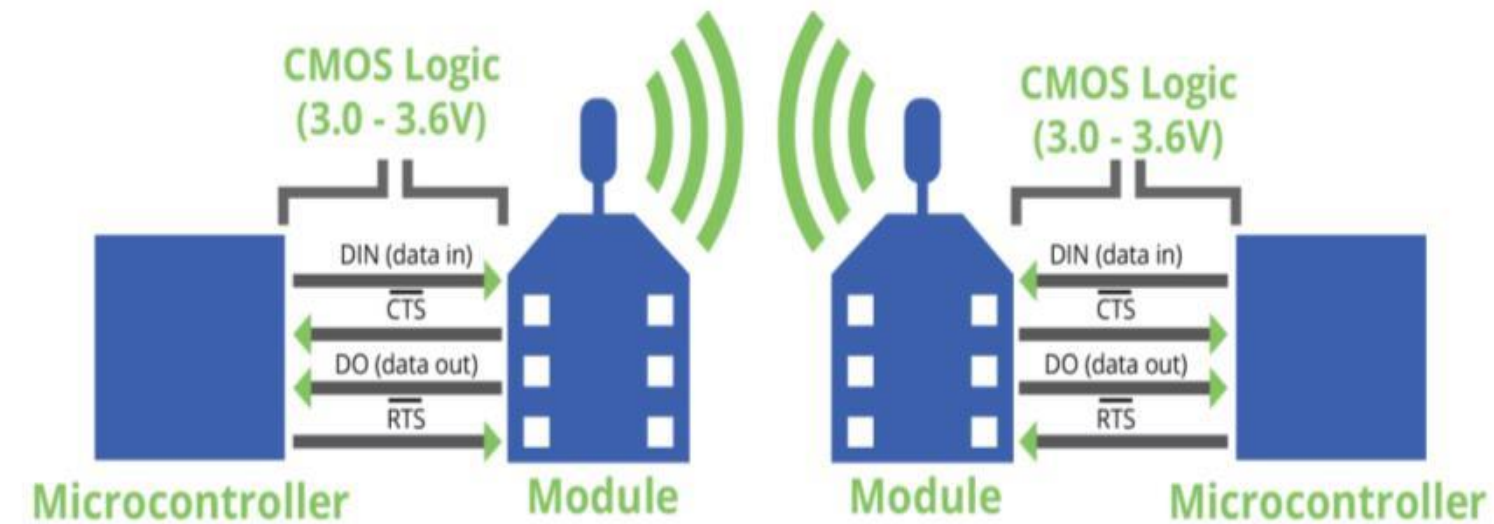


NOTE: DOUBLE-CHECK THAT THE WIRE COLORS MATCH THESE MARKINGS. INCORRECT INSTALLATION OR POLARITY MAY DAMAGE THE ARDUINO BOARD. THE BLUETOOTH MODULE IS PRESET TO A BAUD RATE OF 115200 FOR YOUR CONVENIENCE, BUT YOU MAY CHANGE THE SETTINGS IF NEEDED.

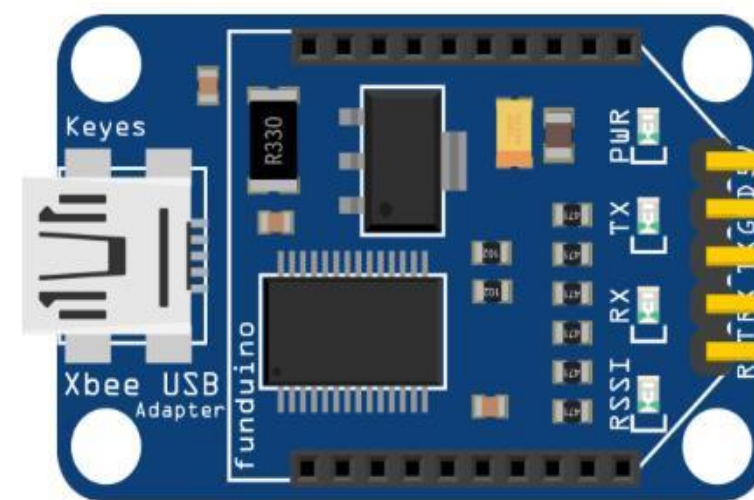
SERIAL RADIO CONFIGURATION



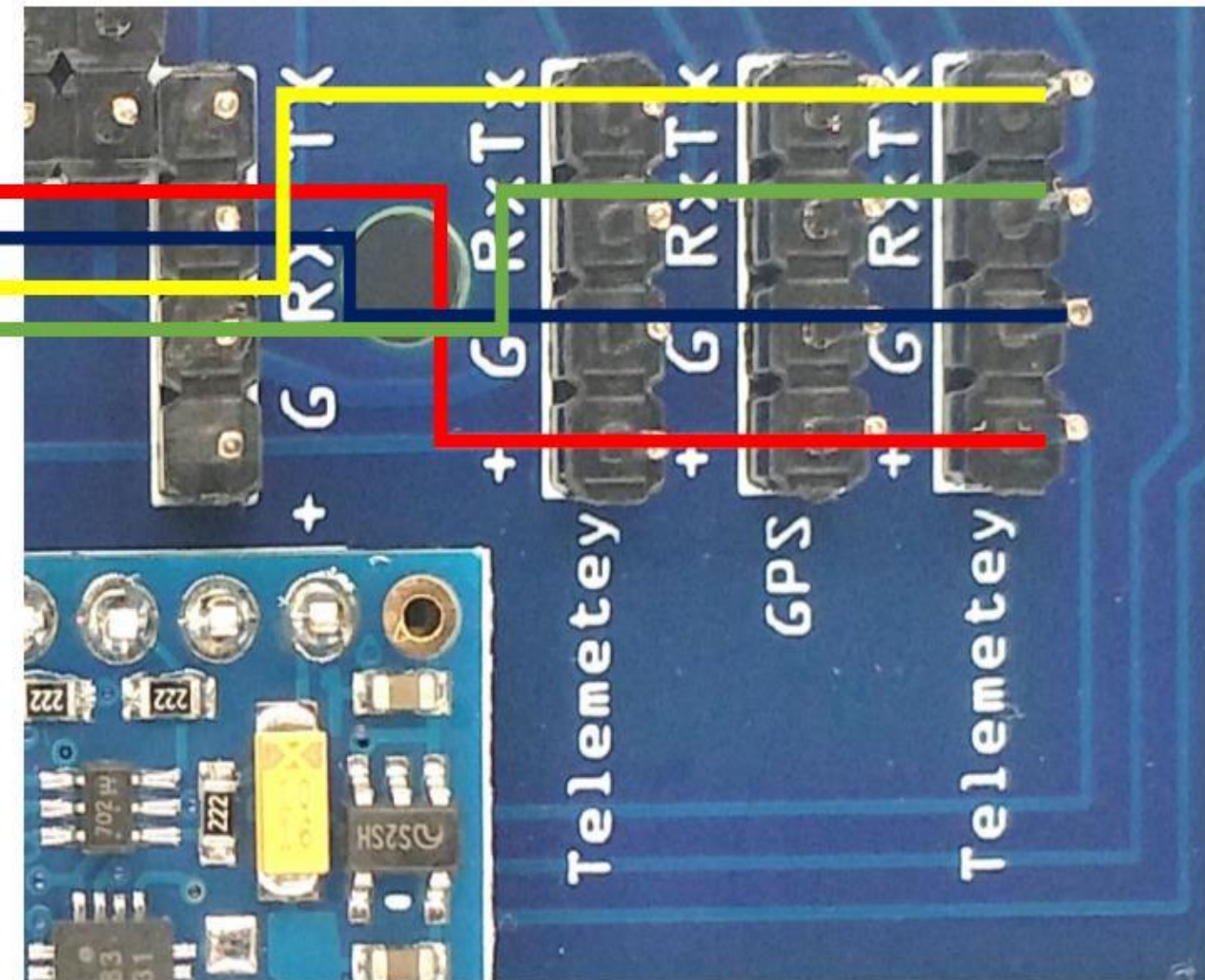
38400 FOR XBEE RADIO



GET THE USB MODULE WITH
BOOT AND RESET BUTTON AS
YOU MAY NEED TO RESET THE
XBEE WHEN UPDATING
FIRMWARE



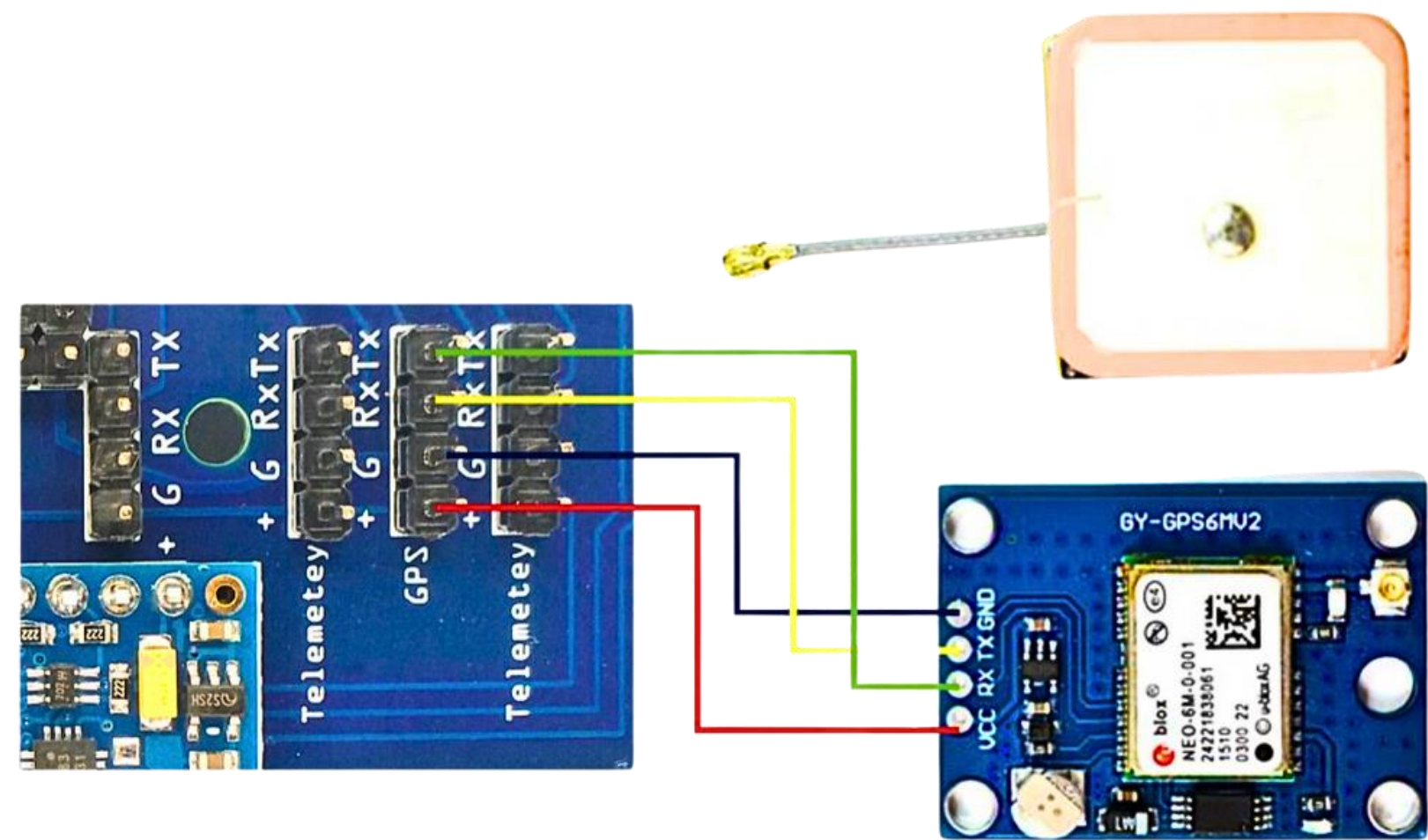
VCC >> +
GND >> G
TX >> TX
RX >> RX



GPS CONFIGURATION

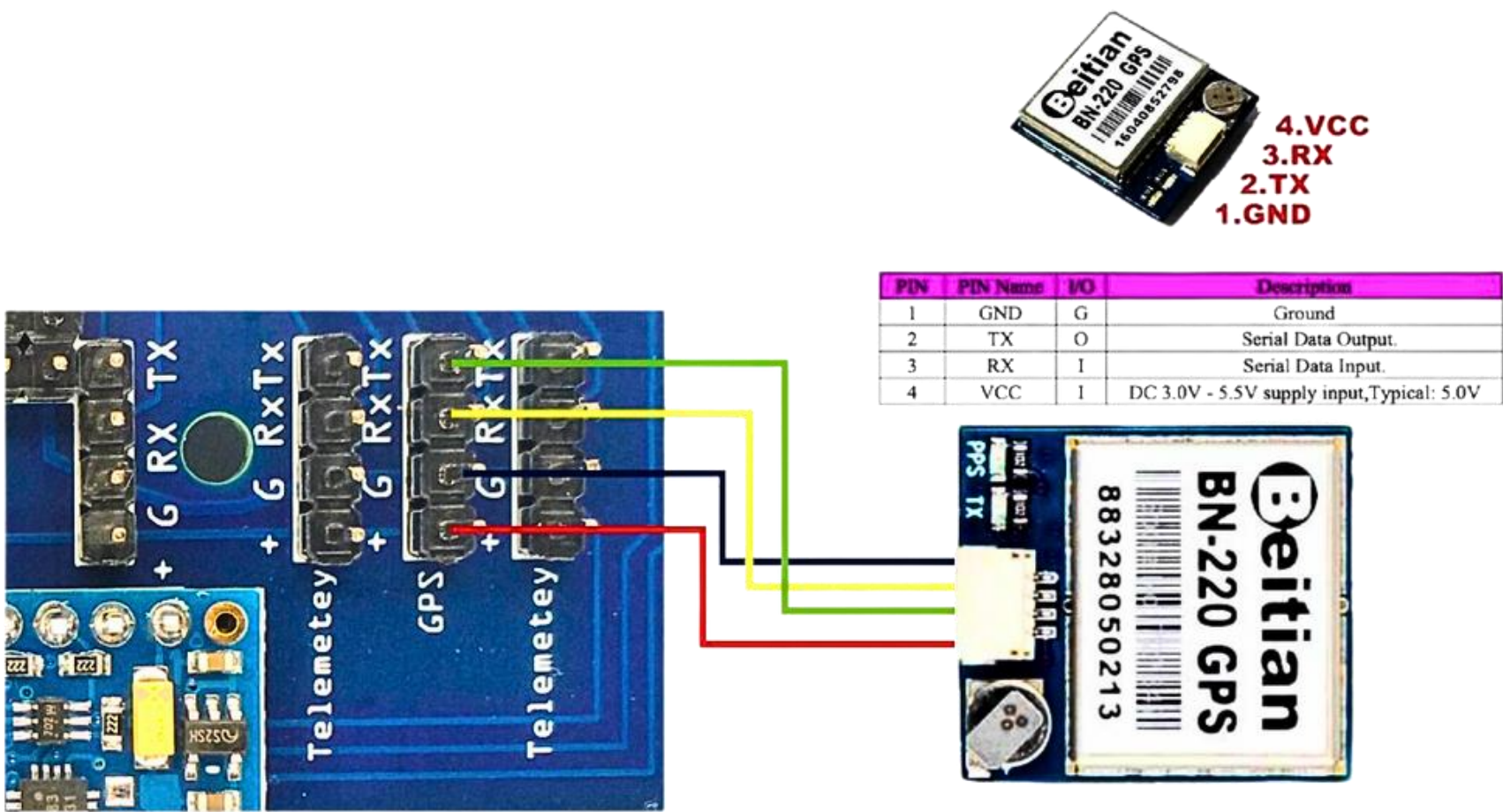
THE **TELEMETRY MODULE** INCLUDES PINS LABELED RX, TX, GND, AND VCC, WHICH CORRESPOND TO THE GPS MODULE'S MATCHING PINS.

TO CONNECT THESE COMPONENTS, COLOR-CODED WIRES CLARIFY THESE CONNECTIONS, WITH **YELLOW** INDICATING **RX TO TX**, **GREEN** FOR **TX TO RX**, **BLACK** FOR **GROUND (GND)**, AND **RED** FOR **POWER (VCC)**.



THE **BEITIAN BN-220 GPS MODULE** SHOWS A SPECIFIC PINOUT TABLE THAT DESCRIBES EACH PIN'S FUNCTION:

- PIN 1 IS GND (GROUND)**
- PIN 2 IS TX (DATA OUTPUT)**
- PIN 3 IS RX (DATA INPUT)**
- PIN 4 IS VCC (POWER SUPPLY RANGES FROM 3.3V TO 5.0V)**



RECEIVER TYPES PROTOCOL

SERIALRECEIVER

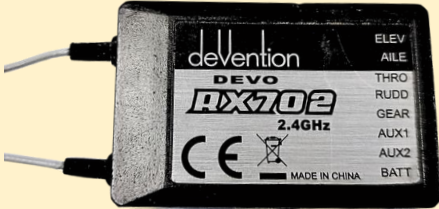


PPM RECEIVER



PWM RECEIVER

RECEIVER TYPE CONFIGURATIONS

RX > SBUS INPUT	FUTABA FORMAT	JR FORMAT	WALKERA FORMAT	GRAUPNER FORMAT	MEGA 2560
	AETR	TAER	EATR	ERTA	INPUT
					
THROTTLE	CH3	CH1	CH3	CH3	A8
AILERON	CH1	CH2	CH2	CH4	A9
ELEVATOR	CH2	CH3	CH1	CH1	A10
RUDDER	CH4	CH4	CH4	CH2	A11
AUX 1	CH5	CH5	CH5	CH5	A12
AUX 2	CH6	CH6	CH6	CH6	A13
AUX 3	CH7	CH7	CH7	CH7	A14
AUX 4	CH8	CH8	CH8	CH8	A15

RECEIVER TYPE CONFIGURATIONS

RX > SBUS INPUT	FUTABA FORMAT	JR FORMAT	WALKERA FORMAT	GRAUPNER FORMAT	UNO
	AETR	TAER	EATR	ERTA	INPUT
					
THROTTLE	CH3	CH1	CH3	CH3	D2
AILERON	CH1	CH2	CH2	CH4	D4
ELEVATOR	CH2	CH3	CH1	CH1	D5
RUDDER	CH4	CH4	CH4	CH2	D6
AUX 1	CH5	CH5	CH5	CH5	D7
AUX 2	CH6	CH6	CH6	CH6	D8
AUX 3	CH7	CH7	CH7	CH7	N/A
AUX 4	CH8	CH8	CH8	CH8	N/A

OTHER RECEIVER TYPE

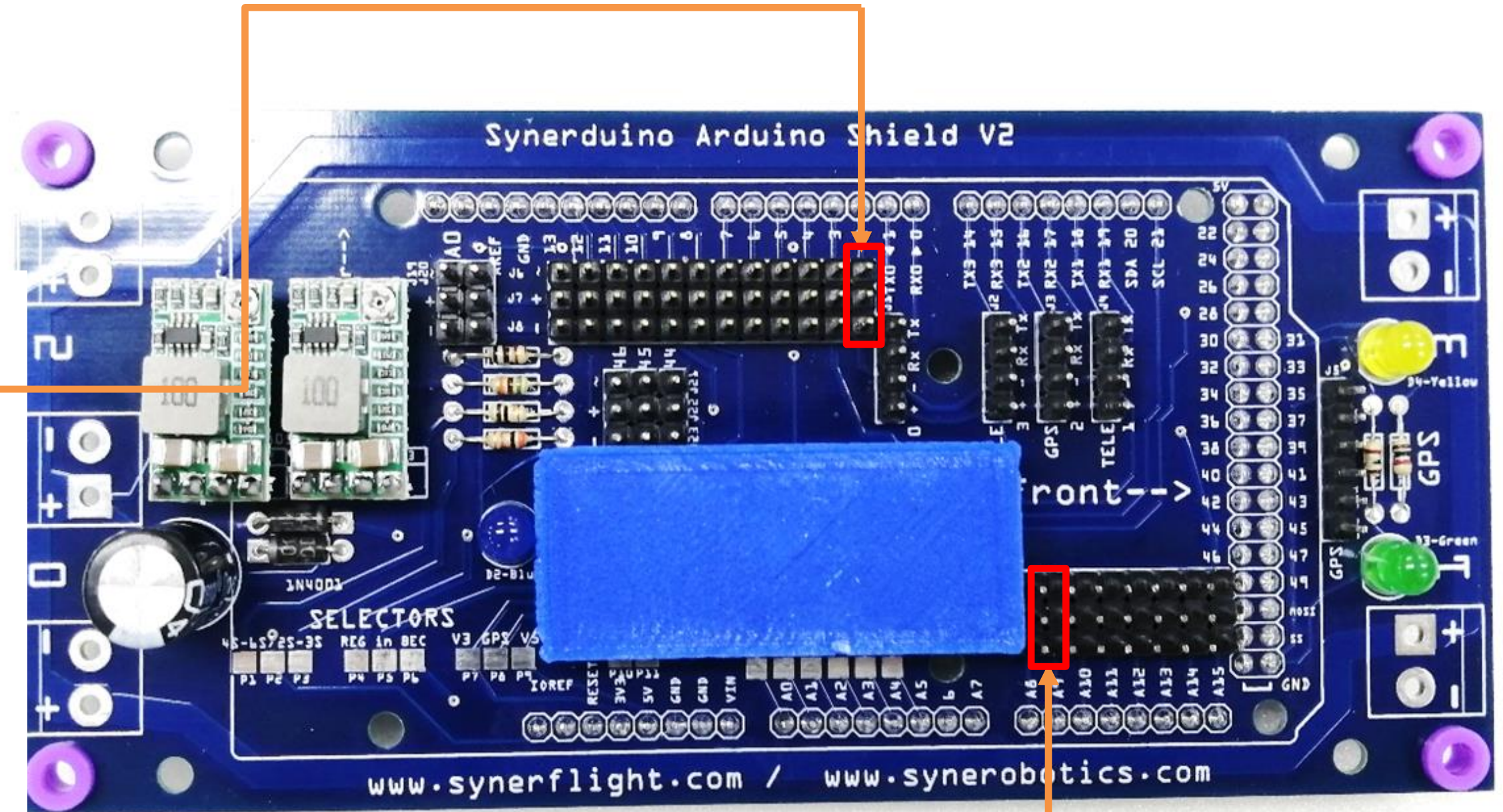
PPM Receiver



Pin D2 for Uno



Pin A8 for Mega



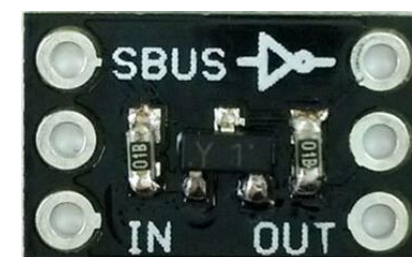
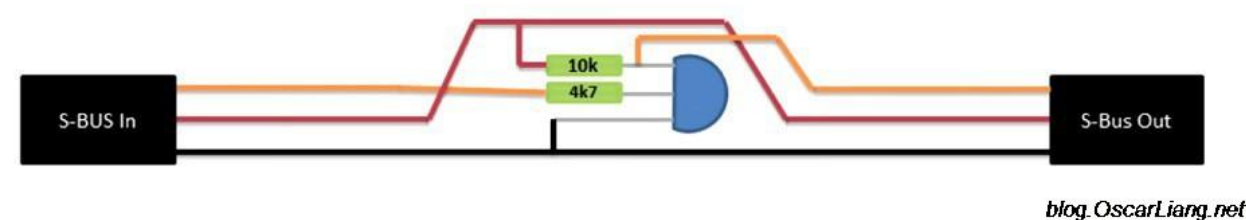
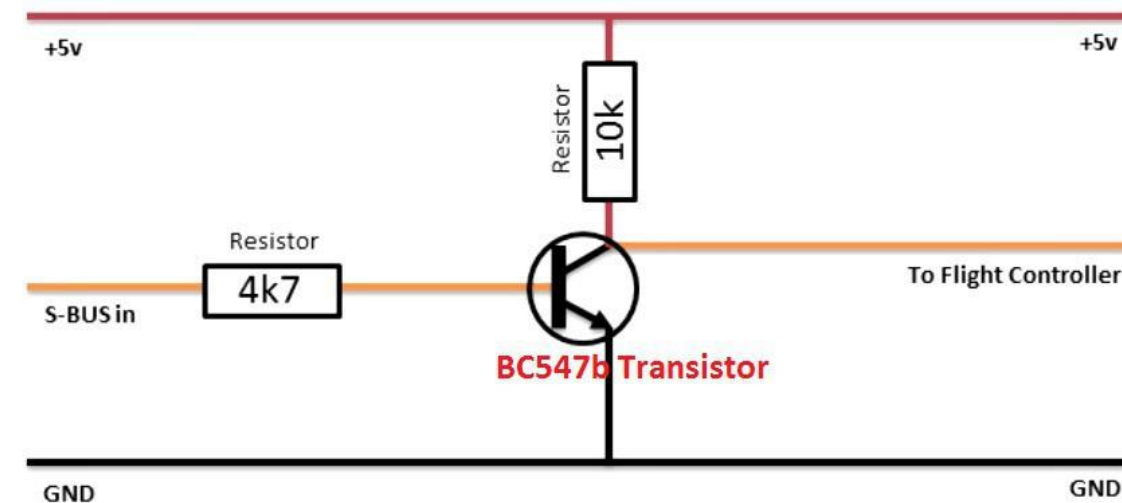
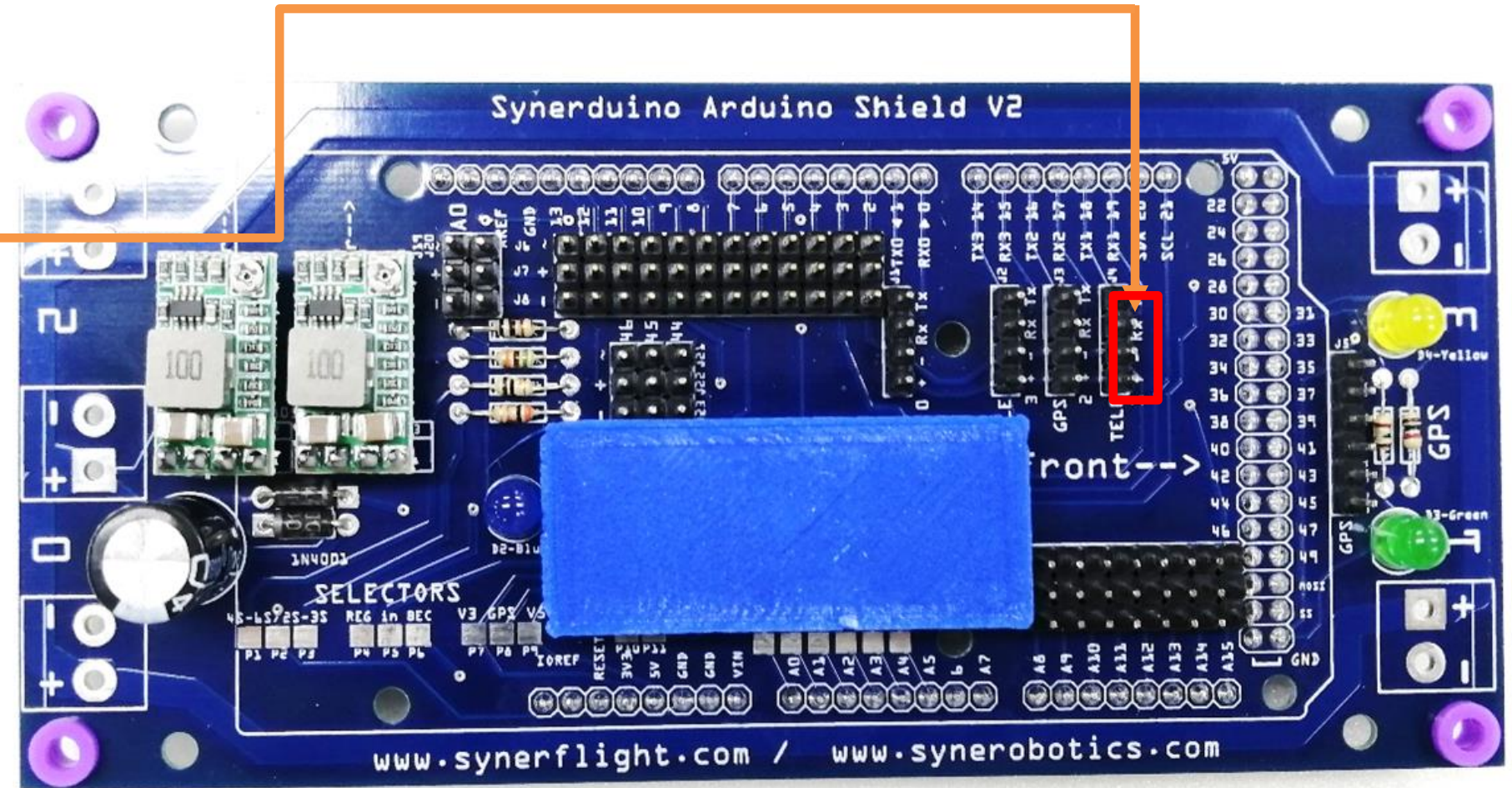
OTHER RECEIVER TYPE

SBUS Receiver



RX 1 Telemetry

The SBUS system uses Futaba protocol and should be compatible with Most SBUS Receivers



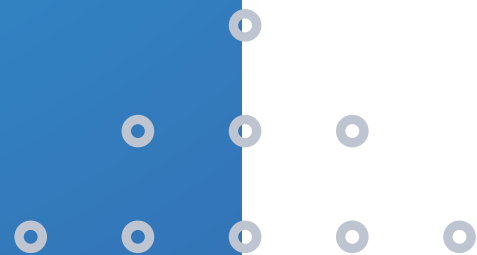
SBUS Inverter

Should there be issues in Signal Inversion an SBUS inverter may be use

You can tell if the RC control is not being read

Most modern Receivers now comes with Serial Protocol as they are faster than the old PWM or PPM standard and its now the Modern defacto for Receiver to Flight Control Board communication

SOFTWARE SETUP



Synerduino KWAD .ino

From here you require to download the Arduino IDE sketch

Multicopter Ino (2024) (Support M9-M10 NMEA , M7-M8 UBX , Home Reset)

Synerduino Kwad 02 09 2024

Multicopter Legacy Ino (2020) (Support M5-M6 NMEA , M7-M8 UBX)

(Arduino 1.8.5) SynerduinoKwad4-GY801-GY91

(Arduino 1.8.16) SynerduinoKwad4-GY801-GY91-1.8.16

(Arduino 1.8.16 – 2.0.0) SynerduinoGY91-1.8.6-2.0.0

(For UNO boards)Synerduino-Uno-GY91-801

<https://synerflight.com/drone-shield/>

See the Synerflight.com website for new updates of the software and click on the download tab

This houses the bulk of that the Arduino Drones codes

TYPE OF MULTICOPTER



CONFIG.H

```
MultiWii - config.h | Arduino 1.8.2
File Edit Sketch Tools Help

MultiWii Alarms.cpp Alarms.h EEPROM.cpp EEPROM.h GPS.cpp GPS.h IMU.cpp IMU.h LCD.cpp LCD.h MultiWii.cpp MultiWii.h Output.cpp Output.h Protocol.cpp Protocol.h RX.cpp RX.h Sensors.cpp Sensors.h

/*****
/*****/

/***** The type of multicopter *****/

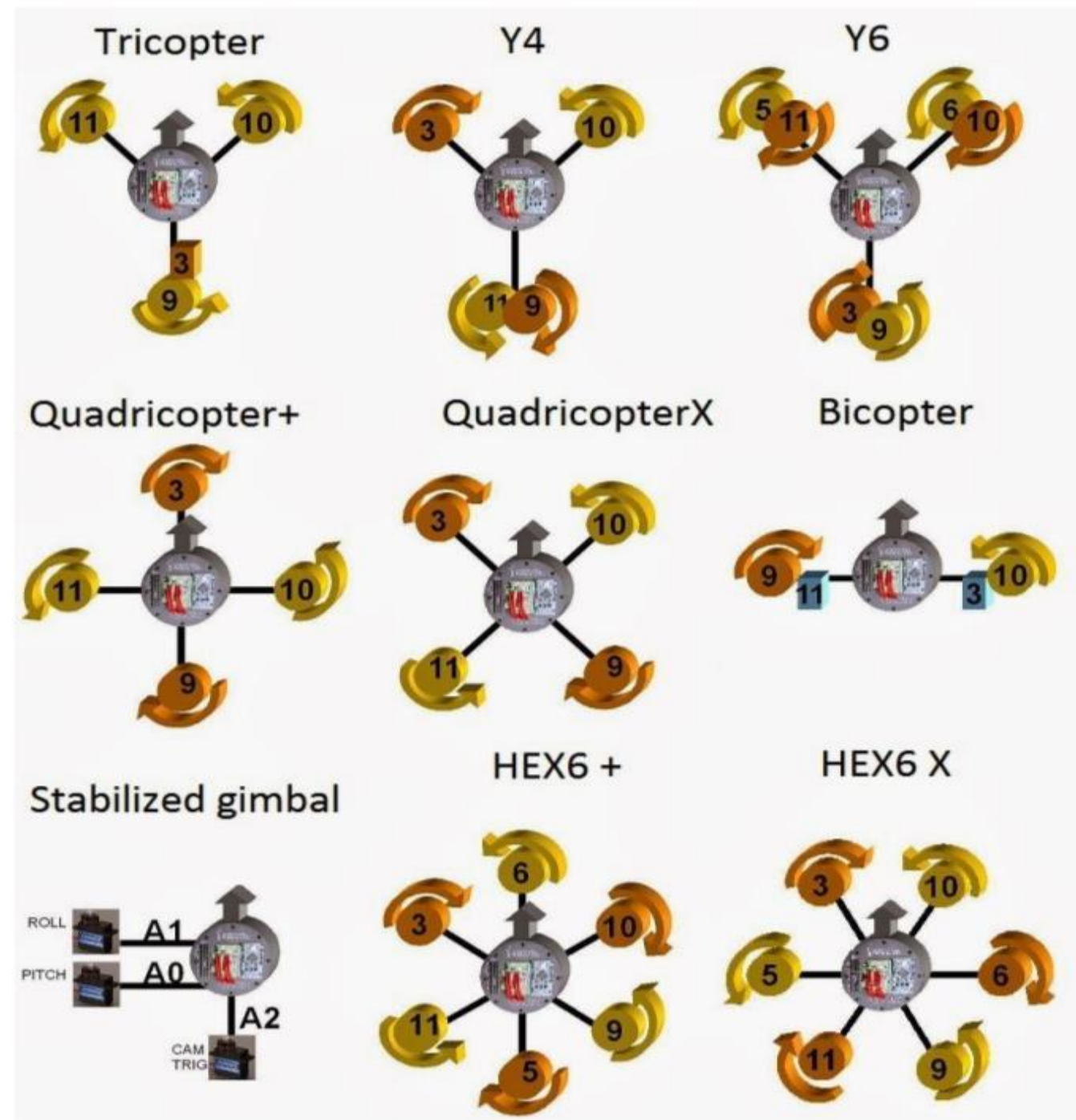
#define GIMBAL
#define BI
#define TRI
#define QUADP
#define QUADX
#define Y4
#define Y6
#define HEX6
#define HEX6X
#define HEX6H // New Model
#define OCTOX8
#define OCTOFLATP
#define OCTOFLATX
#define FLYING_WING
#define VTAIL4
#define AIRPLANE
#define SINGLECOPTER
#define DUALCOPTER
#define HELI_120_CCPM
#define HELI_90_DEG

/***** Motor minthrottle *****/
/* Set the minimum throttle command sent to the ESC (Electronic Speed Controller)
   This is the minimum value that allow motors to run at a idle speed */
#define MINTHROTTLE 1300 // for Turnigy Plush ESCs 10A

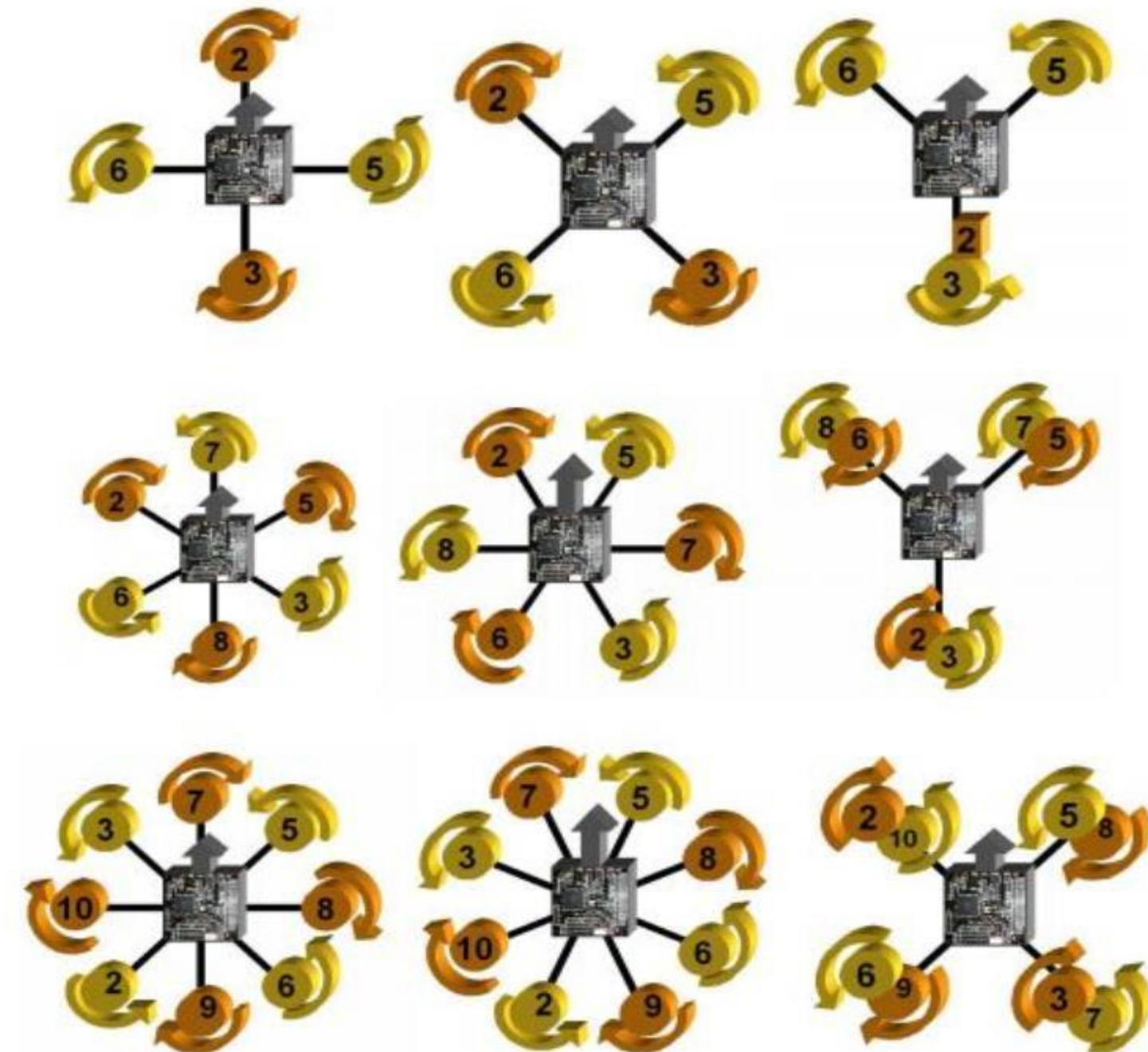
Arduino/Genuino Uno on COM41
8:54 PM
13/02/2020
```

PIN ARRANGMENT FRAME TYPES

CONFIG.H



UNO 328



MEGA 2560

PWM Pins arrangement D2-D10 / PWM Output

MIX TABLE



OUTPUT.CPP

```
MultiWii - Output.cpp | Arduino 1.8.2
File Edit Sketch Tools Help

MultiWii Alarms.cpp Alarms.h EEPROM.cpp EEPROM.h GPS.cpp GPS.h IMU.cpp IMU.h LCD.cpp LCD.h MultiWii.cpp MultiWii.h Output.cpp Output.h Protocol.cpp Protocol.h RX.cpp RX.h Sensors.cpp Sensors.h

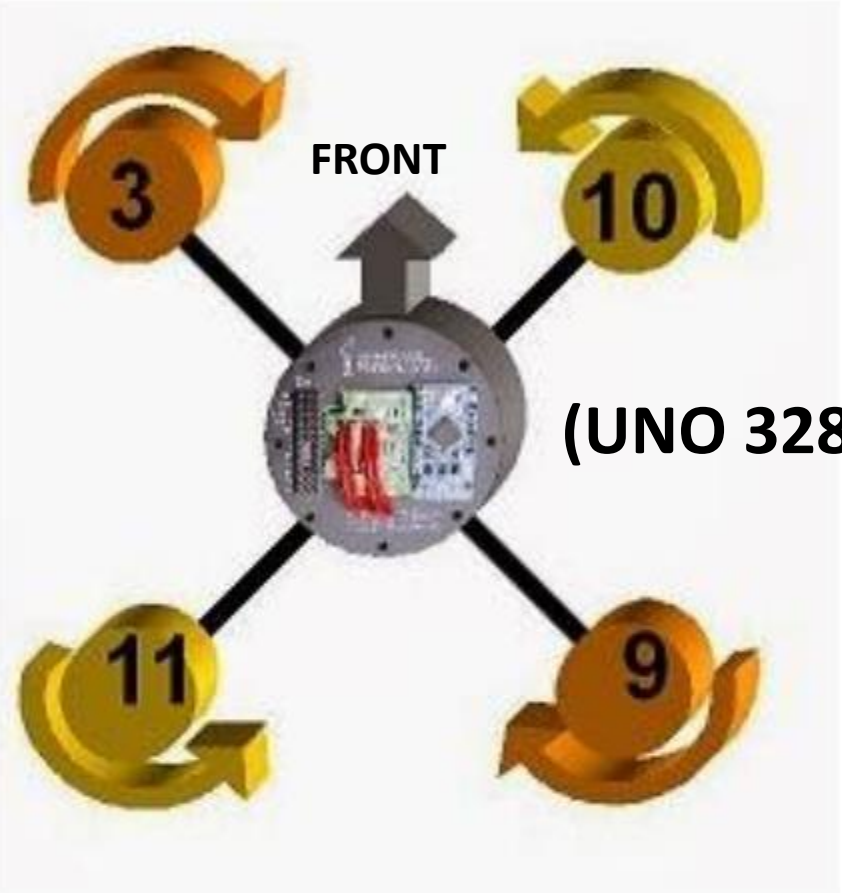
/***** main Mix Table *****/
#ifdef MY_PRIVATE_MIXING
#include MY_PRIVATE_MIXING
#elif defined( BI )
motor[0] = PIDMIX(+1, 0, 0); //LEFT
motor[1] = PIDMIX(-1, 0, 0); //RIGHT
servo[4] = (SERVODIR(4,2) * axisPID[YAW]) + (SERVODIR(4,1) * axisPID[PITCH]) + get_middle(4); //LEFT
servo[5] = (SERVODIR(5,2) * axisPID[YAW]) + (SERVODIR(5,1) * axisPID[PITCH]) + get_middle(5); //RIGHT
#elif defined( TRI )
motor[0] = PIDMIX( 0,+4/3, 0); //REAR
motor[1] = PIDMIX(-1,-2/3, 0); //RIGHT
motor[2] = PIDMIX(+1,-2/3, 0); //LEFT
servo[5] = (SERVODIR(5, 1) * axisPID[YAW]) + get_middle(5); //REAR
#elif defined( QUADP )
motor[0] = PIDMIX( 0,+1,-1); //REAR
motor[1] = PIDMIX(-1, 0,+1); //RIGHT
motor[2] = PIDMIX(+1, 0,+1); //LEFT
motor[3] = PIDMIX( 0,-1,-1); //FRONT
#elif defined( QUADX )
motor[0] = PIDMIX(-1,+1,-1); //REAR_R
motor[1] = PIDMIX(-1,-1,+1); //FRONT_R
motor[2] = PIDMIX(+1,+1,+1); //REAR_L
motor[3] = PIDMIX(+1,-1,-1); //FRONT_L
#elif defined( Y4 )
motor[0] = PIDMIX(+0,+1,-1); //REAR_1 CW
motor[1] = PIDMIX(-1,-1, 0); //FRONT_R CCW
motor[2] = PIDMIX(+0,+1,+1); //REAR_2 CCW
motor[3] = PIDMIX(+1,-1, 0); //FRONT_L CW
#elif defined( V6 )
```

Mix Table shows the motors setup on input this is also helpful for those custom airframe designs require special mixing

OUTPUT.CPP

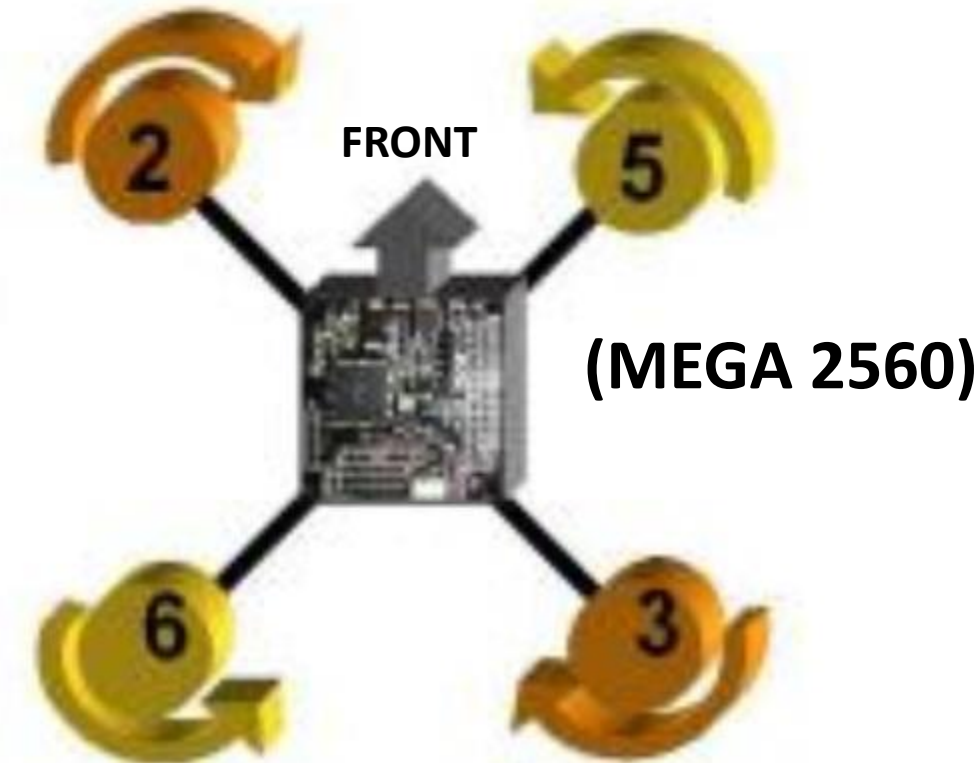
Roll Right Pitch Forward Yaw Right

Motor [3]



Motor [2]

Motor [3]



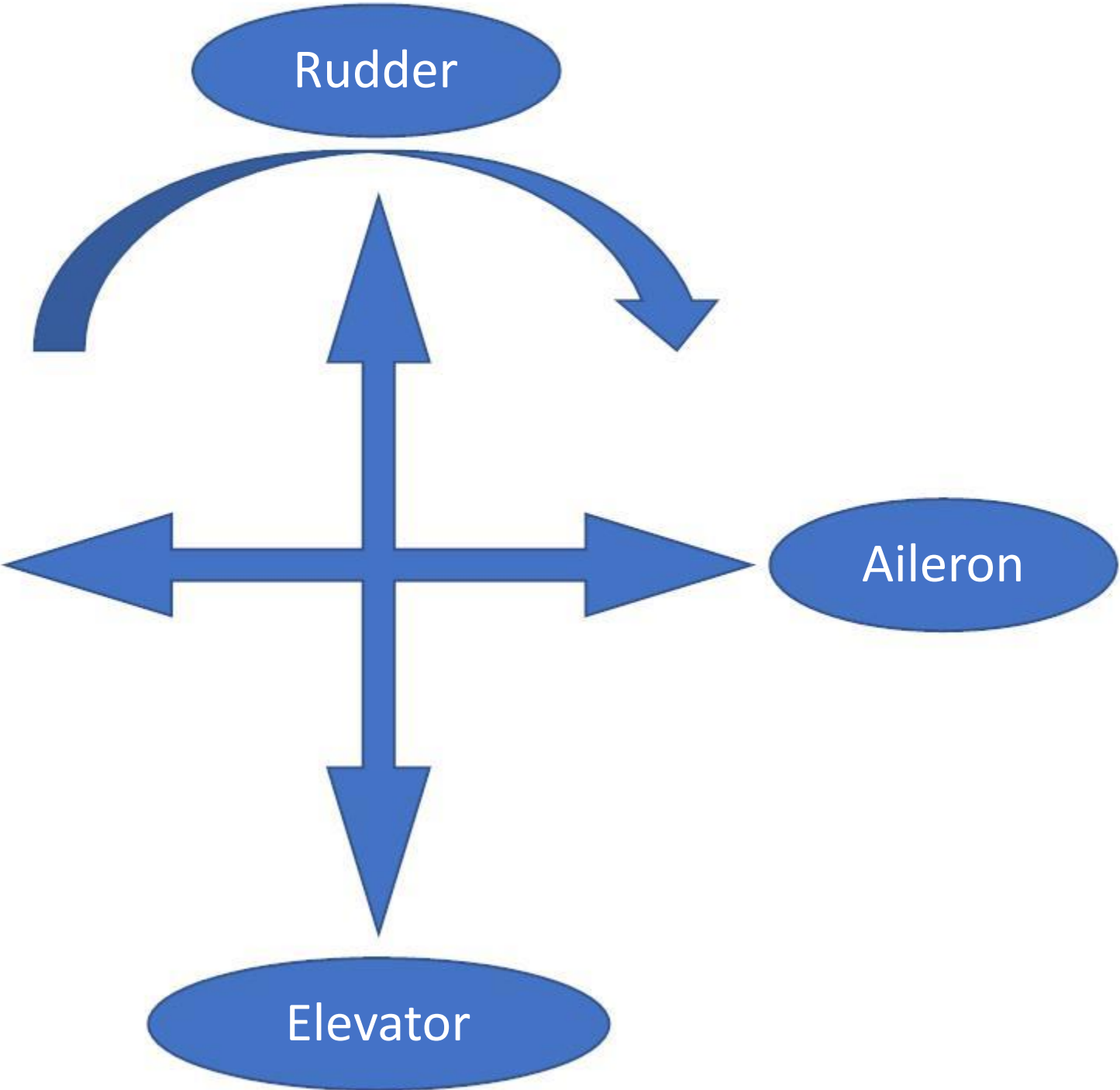
Motor [2]

Motor [1]

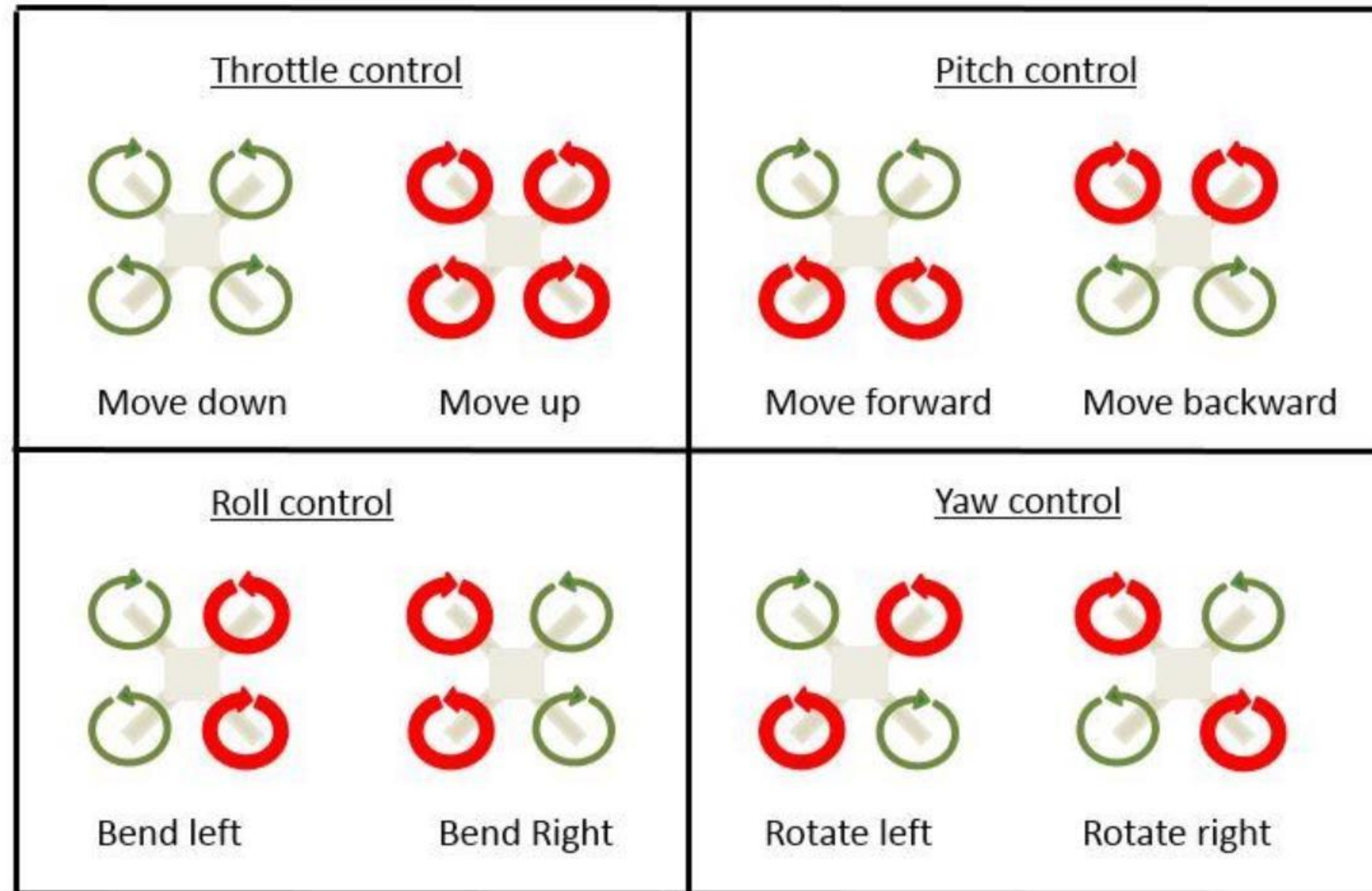
Motor [0]

Motor [1]

Motor [0]



MOTOR MIXING



 Normal Speed (-)

 High Speed (+)

IDLE THROTTLE

CONFIG.H



SynerduinoKwad3-GY801-InvertedMag-1.8.16-M9-10 - config.h | Arduino 1.8.18

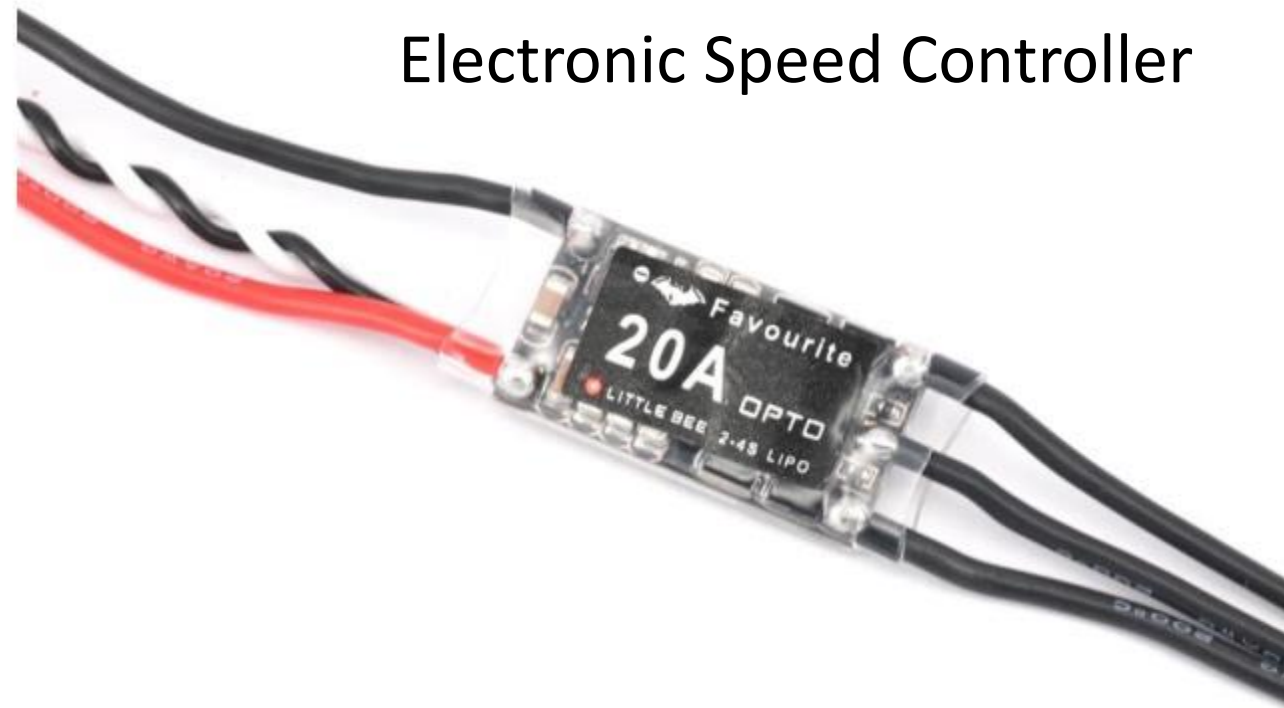
File Edit Sketch Tools Help

```
✓ ↻ 📄 ⬆️ ⬇️
SynerduinoKwad3-GY801-InvertedMag-1.8.16-M9-10  Alarms.cpp  Alarms.h  EEPROM.cpp  EEPROM.h  GPS.cpp  GPS.h  IMU.cpp  IMU.h  LCD.cpp  LCD.h  MultiWii.cpp  MultiWii.h  Output.cpp  Output.h  Protocol.cpp  Protoco...
50  // #define AIRPLANE
51  // #define SINGLECOPTER
52  // #define DUALCOPTER
53  // #define HELI_120_CCPM
54  // #define HELI_90_DEG
55
56  /***** Motor minthrottle *****/
57  /* Set the minimum throttle command sent to the ESC (Electronic Speed Controller)
58     This is the minimum value that allow motors to run at a idle speed */
59  // #define MINTHROTTLE 1300 // for Turnigy Plush ESCs 10A
60  // #define MINTHROTTLE 1120 // for Super Simple ESCs 10A
61  // #define MINTHROTTLE 1064 // special ESC (simonk)
62  // #define MINTHROTTLE 1050 // for brushed ESCs like ladybird
63  #define MINTHROTTLE 1150 // (*) (**)
64
65  /***** Motor maxthrottle *****/
66  /* this is the maximum value for the ESCs at full power, this value can be increased up to 2000 */
67  #define MAXTHROTTLE 1850
68
69  /***** Mincommand *****/
70  /* this is the value for the ESCs when they are not armed
71     in some cases, this value must be lowered down to 900 for some specific ESCs, otherwise they failed to initiate */
72  #define MINCOMMAND 1000
73
74  /***** I2C speed for old WMP config (useless config for other sensors) *****/
75  #define I2C_SPEED 100000L //100kHz normal mode, this value must be used for a genuine WMP
76  // #define I2C_SPEED 400000L //400kHz fast mode, it works only with some WMP clones
77
78  /***** Internal i2c Pullups *****/
79  /* enable internal I2C pull ups (in most cases it is better to use external pullups) */
80  // #define INTERNAL_I2C_PULLUPS
81
```

IDLE THROTTLE

CONFIG.H

Electronic Speed Controller



Brushless Motor



1500

Idle Speed

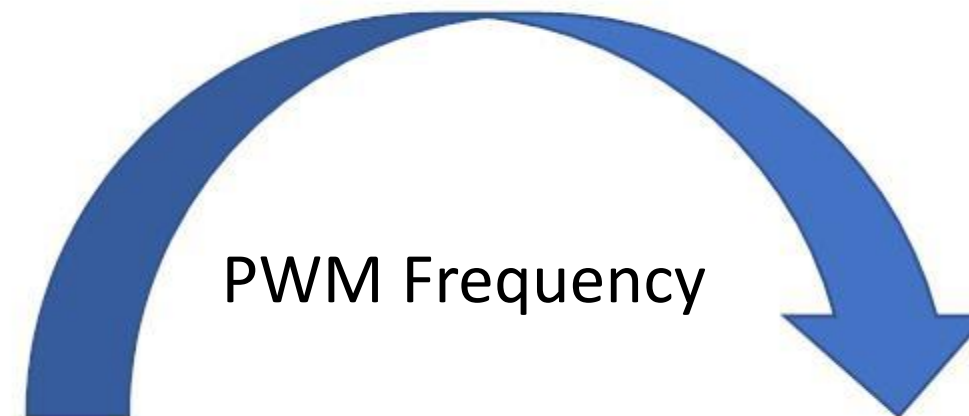
MINTHROTTLE 1150

MINCOMMAND 800 - 1100

PWM Frequency

MAXTHROTTLE 1850

1900 - 2000



CONFIG.H



SELECTING THE SYNERDUINO BOARD

SynerduinoKwad3-GY801-InvertedMag-1.8.16-M9-10 - config.h | Arduino 1.8.18

File Edit Sketch Tools Help

SynerduinoKwad3-GY801-InvertedMag-1.8.16-M9-10

Alarms.cpp

Alarms.h

EEPROM.cpp

EEPROM.h

GPS.cpp

GPS.h

IMU.cpp

IMU.h

LCD.cpp

LCD.h

MultiWii.cpp

MultiWii.h

Output.cpp

Output.h

Protocol.cpp

Protocol.h

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```
140 // #define PROTO_DIY // 10DOF mega board
141 // #define IOI_MINI_MULTIWII // www.bambucopter.com
142 // #define Bobs_6DOF_V1 // BobsQuads 6DOF V1 with ITG3200 & BMA180
143 // #define Bobs_9DOF_V1 // BobsQuads 9DOF V1 with ITG3200, BMA180 & HMC5883L
144 // #define Bobs_10DOF_BMP_V1 // BobsQuads 10DOF V1 with ITG3200, BMA180, HMC5883L & BMP180 - BMP180 is software compatible with BMP085
145 // #define FLYDUINO_MPU // MPU6050 Break Out onboard 3.3V reg
146 // #define CRIUS_AIO_PRO
147 // #define DESQUARED6DOFV2GO // DESquared V2 with ITG3200 only
148 // #define DESQUARED6DOFV4 // DESquared V4 with MPU6050
149 // #define LADYBIRD
150 // #define MEGAWAP_V2_STD // available here: http://www.multircshop.com <- confirmed by Alex
151 // #define MEGAWAP_V2_ADV
152 // #define HK_MultiWii_SE_V2 // Hobbyking board with MPU6050 + HMC5883L + BMP085
153 // #define HK_MultiWii_328P // Also labeled "Hobbybro" on the back. ITG3205 + BMA180 + BMP085 + NMC5583L + DSM2 Connector http://www.hobbyking.com
154 // #define RCNet_FC // RCNet FC with MPU6050 and MS561101BA http://www.rcnet.com
155 // #define RCNet_FC_GPS // RCNet FC with MPU6050 + MS561101BA + HMC5883L + UBLOX GPS http://www.rcnet.com
156 // #define FLYDU_ULTRA // MEGA+10DOF+MT3339 FC
157 // #define DIYFLYING_MAGE_V1 // diyflying 10DOF mega board with MPU6050 + HMC5883L + BMP085 http://www.indoor-flying.hk
158 // #define MultiWii_32U4_SE // Hextronik MultiWii_32U4_SE
159 // #define MultiWii_32U4_SE_no_baro // Hextronik MultiWii_32U4_SE without the MS561101BA to free flash-memory for other functions
160 // #define Flyduino9DOF // Flyduino 9DOF IMU MPU6050+HMC5883L
161 // #define Nano_Plane // Multiwii Plane version with tail-front LSM330 sensor http://www.radiosait.ru/en/page_5324.html
162 // #define SYNERDUINO_GY801_V1 // Synerduino Kwad Shield V1 GY801 (MMC) http://www.synerflight.com
163 // #define SYNERDUINO_GY801_V2 // Synerduino Kwad Shield V2 GY801 (MMC) (reverse Mag) http://www.synerflight.com
164 // #define SYNERDUINO_GY91_V1 // Synerduino Kwad Shield V1 GY91 http://www.synerflight.com
165 // #define SYNERDUINO_GY91_V2_HMC5883 // Synerduino Kwad Shield V2 2024 GY91 http://www.synerflight.com
166 #define SYNERDUINO_GY91_V2_QMC5883 // Synerduino Kwad Shield V2 2024 GY91 http://www.synerflight.com
167 /***** independent sensors *****/
168 /* leave it commented if you already checked a specific board above */
169 /* I2C gyroscope */
170 // #define WMP
171 // #define ITG3050
```

166

Arduino/Genuino Mega or Mega 2560, ATmega2560 (Mega 2560) on COM83

Windows Taskbar

Links Slide5.JPG - Shortcut

4:37 PM 17/11/2024

For the convenience of Synerduino Boards we have included a present on the sketch

To use Combined IMU Boards
UnComment the # Synerduino board base on your version of the board and commend the // Independent Sensors//

// #define SYNERDUINO_GY801_V1

// #define SYNERDUINO_GY801_V2

#define SYNERDUINO_GY91_V2

DEF.H



SynerduinoKwad3 - def.h | Arduino 1.8.5

File Edit Sketch Tools Help

SynerduinoKwad3 Alarms.cpp Alarms.h EEPROM.cpp EEPROM.h GPS.cpp GPS.h IMU.cpp IMU.h LCD.cpp LCD.h MultiWii.cpp MultiWii.h Output.cpp Output.h Protocol.cpp Protocol.h RX.cpp RX.h Sens.cpp

```
#if defined(SYNERDUINO_GY801_V1)
#define L3G4200D // gyro
#define ADXL345 // acc
#define BMP085 // baro
#define MMC5883 // mag
#define ACC_ORIENTATION(X, Y, Z) {imu.accADC[ROLL] = -X; imu.accADC[PITCH] = -Y; imu.accADC[YAW] = Z;}
#define GYRO_ORIENTATION(X, Y, Z) {imu.gyroADC[ROLL] = Y; imu.gyroADC[PITCH] = -X; imu.gyroADC[YAW] = -Z;}
#define MAG_ORIENTATION(X, Y, Z) {imu.magADC[ROLL] = -X; imu.magADC[PITCH] = -Y; imu.magADC[YAW] = -Z;}
#undef INTERNAL_I2C_PULLUPS
#endif

#if defined(SYNERDUINO_GY801_V2)
#define L3G4200D // gyro
#define ADXL345 // acc
#define BMP085 // baro
#define MMC5883 // mag
#define ACC_ORIENTATION(X, Y, Z) {imu.accADC[ROLL] = -X; imu.accADC[PITCH] = -Y; imu.accADC[YAW] = Z;}
#define GYRO_ORIENTATION(X, Y, Z) {imu.gyroADC[ROLL] = Y; imu.gyroADC[PITCH] = -X; imu.gyroADC[YAW] = -Z;}
#define MAG_ORIENTATION(X, Y, Z) {imu.magADC[ROLL] = X; imu.magADC[PITCH] = Y; imu.magADC[YAW] = Z;}
#undef INTERNAL_I2C_PULLUPS
#endif

#if defined(SYNERDUINO_GY91_V1)
#define MPU6050 // gyro
#define BMP280 // baro
#define AK8963 // mag
#define ACC_ORIENTATION(X, Y, Z) {imu.accADC[ROLL] = -X; imu.accADC[PITCH] = -Y; imu.accADC[YAW] = Z;}
#define GYRO_ORIENTATION(X, Y, Z) {imu.gyroADC[ROLL] = Y; imu.gyroADC[PITCH] = -X; imu.gyroADC[YAW] = -Z;}
#define MAG_ORIENTATION(X, Y, Z) {imu.magADC[ROLL] = Y; imu.magADC[PITCH] = Y; imu.magADC[YAW] = -Z;}
#endif
```

1671 - 1641

Arduino/Genuino Mega or Mega 2560, ATmega2560 (Mega 2560) on COM25

2:33 PM 30/09/2021

Board Define orientation can be found in Def.h Tab

IMU Orientations and Sensor definitions

Pls see the Board Specs Data sheets for the installed IMUs onboard



Magnetometer



Barometer

This is the heart of every flight controller AKA the Main 4 ,

Gyro – stabilization on Roll Pitch Yaw Axis

Acc - Horizontal and Vertical stabilization XYZ

Baro – Altitude hold control

Mag – Heading and Compass



Accelerometer



Gyroscope

Each sensor has a corresponding address registry set by manufacturer

You can find it on sensors.ccp tab

CONFIG.H



SELECTING THE SENSORS

SynerduinoKwad3-GY801-InvertedMag-1.8.16-M9-10 - config.h | Arduino 1.8.18

File Edit Sketch Tools Help

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SynerduinoKwad3-GY801-InvertedMag-1.8.16-M9-10 Alarms.cpp Alarms.h EEPROM.cpp EEPROM.h GPS.cpp GPS.h IMU.cpp IMU.h LCD.cpp LCD.h MultiWii.cpp MultiWii.h Output.cpp Output.h Protocol.cpp Proto...

169 /* I2C gyroscope */
170 // #define WMP
171 // #define ITG3050
172 // #define ITG3200
173 // #define MPU3050
174 // #define L3G4200D // (GY801)
175 // #define MPU6050 // combo + ACC (GY91)
176 // #define LSM330 // combo + ACC
177
178 /* I2C accelerometer */
179 // #define MMA7455
180 // #define ADXL345 // (GY801)
181 // #define BMA020
182 // #define BMA180
183 // #define BMA280
184 // #define LIS3LV02
185 // #define LSM303DLx_ACC
186 // #define MMA8451Q
187
188 /* I2C barometer */
189 // #define BMP085 // (GY801)
190 // #define BMP280 // (GY91)
191 // #define MS561101BA
192
193
194 /* I2C magnetometer */
195 // #define HMC5843
196 // #define HMC5883 // (GY801)
197 // #define QMC5883
198 // #define MMC5883 // (GY801)
199 // #define AK8975
200 // #define AK8963 (GY91)

190

Arduino/Genuino Mega or Mega 2560, ATmega2560 (Mega 2560) on COM83

If you decided to do custom sensor selection
Depending on the Version of ic2 sensors installed on the board you got select correct sensors for it to work. Note: comment the the synerduino board selections

To use independent sensor **Comment the // Combined IMU Boards // and uncommend the # Independent Sensors**

Synerduino GY801
#define L3G4200D // gyro
#define ADXL345 // acc
#define BMP085 // baro
#define MMC5883 // mag

Synerduino GY91
#define MPU6050 // gyro
#define BMP280 // baro
#define qmc5883 // mag

190

Arduino/Genuino Mega or Mega 2560, ATmega2560 (Mega 2560) on COM83

SENSOR ORIENTATION

CONFIG.H

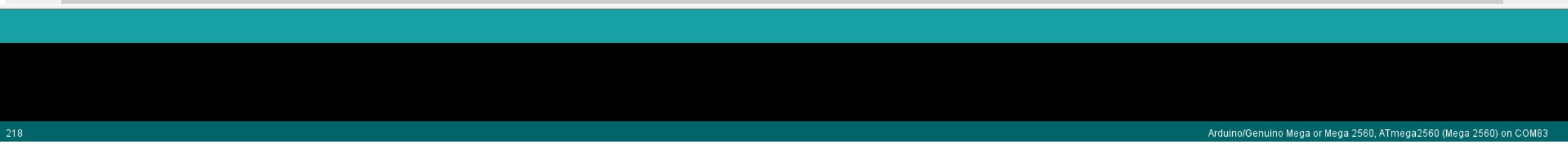
SynerduinoKwad3-GY801-InvertedMag-1.8.16-M9-10 - config.h | Arduino 1.8.18

File Edit Sketch Tools Help



SynerduinoKwad3-GY801-InvertedMag-1.8.16-M9-10 Alarms.cpp Alarms.h EEPROM.cpp EEPROM.h GPS.cpp GPS.h IMU.cpp IMU.h LCD.cpp LCD.h MultiWii.cpp MultiWii.h Output.cpp Output.h Protocol.cpp Protocol.h

```
202
203  /* Sonar */ // for visualization purpose currently - no control code behind
204  //#define SRF02 // use the Devantech SRF i2c sensors
205  //#define SRF08
206  //#define SRF10
207  //#define SRF23
208
209  /* ADC accelerometer */ // for 5DOF from sparkfun, uses analog PIN A1/A2/A3
210  //#define ADCACC
211
212  /* enforce your individual ACC sensor orientation - even overrides board specific defaults */
213  //#define FORCE_ACC_ORIENTATION(X, Y, Z) {imu.accADC[ROLL] = -X; imu.accADC[PITCH] = -Y; imu.accADC[YAW] = Z;} //GY91 GY801
214  /* enforce your individual GYRO sensor orientation - even overrides board specific defaults */
215  //#define FORCE_GYRO_ORIENTATION(X, Y, Z) {imu.gyroADC[ROLL] = Y; imu.gyroADC[PITCH] = -X; imu.gyroADC[YAW] = -Z;} //GY91 GY801
216
217  /* for those with inverted mag orientation - Pls check your Graphs and dashboards see if inputs are correct GY801*/
218  //#define FORCE_MAG_ORIENTATION(X, Y, Z) {imu.magADC[ROLL] = -X; imu.magADC[PITCH] = -Y; imu.magADC[YAW] = -Z;} // GY801 V1
219  //#define FORCE_MAG_ORIENTATION(X, Y, Z) {imu.magADC[ROLL] = X; imu.magADC[PITCH] = Y; imu.magADC[YAW] = Z;} // GY802 V2
220  /* for those with inverted mag orientation - Pls check your Graphs and dashboards see if inputs are correct GY91*/
221  //#define FORCE_MAG_ORIENTATION(X, Y, Z) {imu.magADC[ROLL] = Y; imu.magADC[PITCH] = X; imu.magADC[YAW] = -Z;} // GY91 V1
222  //#define FORCE_MAG_ORIENTATION(X, Y, Z) {imu.magADC[ROLL] = Y; imu.magADC[PITCH] = -X; imu.magADC[YAW] = -Z;} // GY91 V2
223
224  /* Board orientation shift */
225  /* If you have frame designed only for + mode and you cannot rotate FC phisycally for flying in X mode (or vice versa)
226  * you can use one of of this options for virtual sensors rotation by 45 deegres, then set type of multicopter according to flight mode.
227  * Check motors order and directions of motors rotation for matching with new front point! Uncomment only one option! */
228  //#define SENSORS_TILT_45DEG_RIGHT // rotate the FRONT 45 degrees clockwise
229  //#define SENSORS_TILT_45DEG_LEFT // rotate the FRONT 45 degrees counterclockwise
230
231  /*****
232  /*****
233  /***** SECTION 2 - COPTER TYPE SPECIFIC OPTIONS *****/
```



UNCOMMENTING THESE LINES FORCES THE ORIENTATION TO ENFORCE INDIVIDUAL SENSOR ORIENTATION MODE AND IGNORES THE DEFINE BOARDS ORIENTATION ON DEF.H

THIS IS USEFUL FOR SPECIFIC BOARD ALIGNMENT CHANGES OR A EXTERNAL SENSOR ADDON

SENSORS IMU ORIENTATION IS IMPORTANT SEE TO IT THE ACC GYRO AND MAG ALL COMPLIMENT EACH OTHER

For PPM Receiver

Channel Mapping

Uncomment PPM on Throttle

Pin A8 for Mega

Pin D2 for Uno

You may need to uncomment and change the ordering of your channel depending on your Transmitter's model and specification



```
368 // #define EXTENDED_AUX_STATES
369
370
371 /*****
372 /***** special receiver types *****/
373 /*****
374
375 /***** PPM Sum Receiver *****/
376 /* The following lines apply only for specific receiver with only one PPM sum signal, on digital PIN 2
377    Select the right line depending on your radio brand. Feel free to modify the order in your PPM order is different */
378 // #define SERIAL_SUM_PPM PITCH,YAW,THROTTLE,ROLL,AUX1,AUX2,AUX3,AUX4,8,9,10,11 //For Graupner/Spektrum
379 // #define SERIAL_SUM_PPM ROLL,PITCH,THROTTLE,YAW,AUX1,AUX2,AUX3,AUX4,8,9,10,11 //For Robe/Hitec/Futaba
380 // #define SERIAL_SUM_PPM ROLL,PITCH,YAW,THROTTLE,AUX1,AUX2,AUX3,AUX4,8,9,10,11 //For Multiplex
381 // #define SERIAL_SUM_PPM PITCH,ROLL,THROTTLE,YAW,AUX1,AUX2,AUX3,AUX4,8,9,10,11 //For some Hitec/Sanwa/Others
382
383 /* Uncommenting following line allow to connect PPM_SUM receiver to standard THROTTLE PIN on MEGA boards (eg. A8 in CRIUS AIO)*/
384 // #define PPM_ON_THROTTLE
385
386 /***** Spektrum Satellite Receiver *****/
387 /* The following lines apply only for Spektrum Satellite Receiver
388    Spektrum Satellites are 3V devices. DO NOT connect to 5V!
389    For MEGA boards, attach sat grey wire to RX1, pin 19. Sat black wire to ground. Sat orange wire to Mega board's 3.3V (or any other 3V to 3.3V source).
390    For PROMINI, attach sat grey to RX0. Attach sat black to ground. */
391 // #define SPEKTRUM 1024
392 // #define SPEKTRUM 2048
393 // #define RX_SERIAL_PORT 1 // Forced to 0 on Pro Mini and single serial boards; Set to your choice of 0, 1, or 2 on any Mega based board (defaults to 1 on Mega).
394 // ****
395 // Defines that allow a "Bind" of a Spektrum or Compatible Remote Receiver (aka Satellite) via Configuration GUI.
396 // Bind mode will be same as declared above, if your TX is capable.
397 // Ground, Power, and Signal must come from three adjacent pins.
398 // By default, these are Ground=4, Power=5, Signal=6. These pins are in a row on most MultiWii shield boards. Pins can be overridden below.
399 // Normally use 3.3V regulator is needed on the power pin!! If your satellite hangs during bind (blinks, but won't complete bind with a solid light), go direct 5V on all pins.
```

RECEIVER TYPES PROTOCOL

CONFIG.H



For SBUS Receiver

Channel Mapping

Uncomment SBUS
on RX Serial Port 1
(Telemetry 1)

You may need to
uncomment and
change the ordering
of your channel
depending on your
Transmitter's model
and specification

```
392 //*****
393 // Defines that allow a "Bind" of a Spektrum or Compatible Remote Receiver (aka Satellite) via Configuration GUI.
394 // Bind mode will be same as declared above, if your TX is capable.
395 // Ground, Power, and Signal must come from three adjacent pins.
396 // By default, these are Ground=4, Power=5, Signal=6. These pins are in a row on most MultiWii shield boards. Pins can be overridden below.
397 // Normally use 3.3V regulator is needed on the power pin!! If your satellite hangs during bind (blinks, but won't complete bind with a solid light), go direct 5V on all pins.
398 //*****
399 // For Pro Mini, the connector for the Satellite that resides on the FTDI can be unplugged and moved to these three adjacent pins.
400 // #define SPEK_BIND //Un-Comment for Spektrum Satellite Bind Support. Code is ~420 bytes smaller without it.
401 // #define SPEK_BIND_GROUND 4
402 // #define SPEK_BIND_POWER 5
403 // #define SPEK_BIND_DATA 6
404
405 //***** SBUS RECIVER *****/
406 /* The following line apply only for Futaba S-Bus Receiver on MEGA boards or PROMICRO boards.
407 You have to invert the S-Bus-Serial Signal e.g. with a Hex-Inverter like IC SN74 LS 04 */
408 // #define SBUS PITCH,YAW,THROTTLE,ROLL,AUX1,AUX2,AUX3,AUX4,8,9,10,11,12,13,14,15,16,17 // dsm2 orangerx
409 #define SBUS ROLL,PITCH,THROTTLE,YAW,AUX1,AUX2,AUX3,AUX4,8,9,10,11,12,13,14,15,16,17 // T14SG
410 #define RX_SERIAL_PORT 1
411 #define SBUS_MID_OFFSET 988 //SBUS Mid-Point at 1500
412
413 //***** HOTT RECIVER *****/
414 /* Graupner Hott HD */
415 // #define SUMD PITCH,YAW,THROTTLE,ROLL,AUX1,AUX2,AUX3,AUX4
416 // #define RX_SERIAL_PORT 1
417
418 //*****
419 //*****
420 //***** SECTION 4 - ALTERNATE CPUs & BOARDS *****/
421 //*****
422 //*****
423
424 //*****
```

Done Saving.

avrdude done. Thank you.

410 - 409

Arduino Mega or Mega 2560, ATmega2560 (Mega 2560) on COM17

Links ENG 8:48 PM 24/07/2022



AUX PIN

For UNO you need to
define your PPM Aux 2
Pin

```
MultiWii - config.h | Arduino 1.8.2
File Edit Sketch Tools Help

MultiWii Alarms.cpp Alarms.h EEPROM.cpp EEPROM.h GPS.cpp GPS.h IMU.cpp IMU.h LCD.cpp LCD.h MultiWii.cpp MultiWii.h Output.cpp Output.h Protocol.cpp Protocol.h RX.cpp RX.h Sensors.cpp Sensors.h

/***** Promini Specifig Settings *****/
/***** Hexa Motor 5 & 6 Pins *****/
/* PIN A0 and A1 instead of PIN D5 & D6 for 6 motors config and promini config
This mod allow the use of a standard receiver on a pro mini
(no need to use a PPM sum receiver) */
#define A0_A1_PIN_HEX

/***** Aux 2 Pin *****/
/* possibility to use PIN8 or PIN12 as the AUX2 RC input (only one, not both)
it deactivates in this case the POWER PIN (pin 12) or the BUZZER PIN (pin 8) */
#define RCAUXPIN8
#define RCAUXPIN12

/***** Teensy 2.0 Support *****/
/* uncomment this if you use a teensy 2.0 with teensyduino
it needs to run at 16MHz */
#define TEENSY20

/***** Settings for ProMicro, Leonardo and other Atmega32u4 Boards *****/
```

427 Arduino/Genuino Mega or Mega 2560, ATmega2560 (Mega 2560) on COM3D 11:12 AM 11/01/2021

TELEMETRY COM SPEED

CONFIG.H

SERIAL BAUD RATE

WILL DEPEND ON WHAT BAUD YOUR TELEMETRY MODULE ARE SET INTO YOU CAN CHANGE IT TO SUITE THE PORT YOUR DEVICE IS CONNECTED TO.

SERIAL 0 CAN BE USE FOR TELEMETRY GIVEN NOTHING IS CONNECTED TO THE USB AT THIS POINT. AND FIRMWARE MUST BE FLISH PRIOR TO HOOKING UP ANYTHING TO THIS PINS

SERIAL 1 , 3 IS RESERVE FOR TELEMETRY

115200 FOR BLUETOOTH HC-05

38400 FOR XBEE RADIO

57600 for SIK RADIO

SERIAL 2 IS RESERVE FOR GPS

NMEA Baud 57600

SynerduinoKwad3-GY801-InvertedMag-1.8.16-M9-10 - config.h | Arduino 1.8.18

File Edit Sketch Tools Help

SynerduinoKwad3-GY801-InvertedMag-1.8.16-M9-10 Alarms.cpp Alarms.h EEPROM.cpp EEPROM.h GPS.cpp GPS.h IMU.cpp IMU.h LCD.cpp LCD.h MultiWii.cpp MultiWii.h Output.cpp Output.h Protocol.cpp Proto...

```
509 /***** SECTION 5 - ALTERNATE SETUP *****/
510 /*****
511 /*****
512
513 /***** Serial com speed *****/
514 /* This is the speed of the serial interfaces */
515 /*Serial 1 Bluetooth 115200 */
516 /*Serial 2 GPS */
517 /*Serial 3 SIK/Xbee 38400*/
518 /* This is the speed of the serial interfaces */
519 #define SERIAL0_COM_SPEED 115200
520 // #define SERIAL3_COM_SPEED 115200
521 #define SERIAL2_COM_SPEED 115200
522 // #define SERIAL1_COM_SPEED 115200
523
524 /*Serial 1 Bluetooth Serial 2 GPS Serial 3 Telemetry*/
525 #define SERIAL3_COM_SPEED 38400
526 #define SERIAL1_COM_SPEED 57600
527
528
529 /* when there is an error on I2C bus, we neutralize the values during a short time. expressed in microseconds
530 it is relevent only for a conf with at least a WMP */
531 #define NEUTRALIZE_DELAY 100000
532
533 /*****
534 /***** Gyro filters *****/
535 /*****
536
537 /***** Lowpass filter for some gyros *****/
538 /* ITG3200 & ITG3205 Low pass filter setting. In case you cannot eliminate all vibrations to the Gyro, you can try
539 to decrease the LPF frequency, only one step per try. As soon as twitching gone, stick with that setting.
540 It will not help on feedback wobbles, so change only when copter is randomly twitching and all dampening and
```

519 Arduino/Genuino Mega or Mega 2560, ATmega2560 (Mega 2560) on COM83



MultiWii - config.h | Arduino 1.8.2

File Edit Sketch Tools Help

MultiWii Alarms.cpp Alarms.h EEPROM.cpp EEPROM.h GPS.cpp GPS.h IMU.cpp IMU.h LCD.cpp LCD.h MultiWii.cpp MultiWii.h Output.cpp Output.h Protocol.cpp Protocol.h RX.cpp RX.h Sensors.cpp

```
/* introduce a deadband around the stick center
Must be greater than zero, comment if you dont want a deadband on roll, pitch and yaw */
#define DEADBAND 6

/* Enable this for using GPS simulator (NMEA only) */
#define GPS_SIMULATOR

/* GPS using a SERIAL port
if enabled, define here the Arduino Serial port number and the UART speed
note: only the RX PIN is used in case of NMEA mode, the GPS is not configured by multiwii
in NMEA mode the GPS must be configured to output GGA and RMC NMEA sentences (which is generally the default conf for most GPS devices)
at least 5Hz update rate. uncomment the first line to select the GPS serial port of the arduino */

#define GPS_SERIAL 2 // should be 2 for flyduino v2. It's the serial port number on arduino MEGA
// must be 0 for PRO_MINI (ex GPS_PRO_MINI)
// note: Now a GPS can share MSP on the same port. The only constrain is to not use it simultaneously, and use the same port speed.

// avoid using 115200 baud because with 16MHz arduino the 115200 baudrate have more than 2% speed error (57600 have 0.8% error)
#define GPS_BAUD 38400 // ublox 8 new standard
#define GPS_BAUD 9600
#define GPS_BAUD 57600 // GPS_BAUD will override SERIALx_COM_SPEED for the selected port (my ublox 6)
#define GPS_BAUD 115200
```

Done Saving.

676 Arduino/Genuino Uno on COM41

4:05 PM 20/02/2020

**Set GPS BAUD to 57600
Or its matching baud
as configured to the
GPS module**



SynerduinoKwad3-GY91-1.8.16-M9-10 - config.h | Arduino 1.8.18

File Edit Sketch Tools Help

✓ ↻ 📄 ⬆ ⬇

SynerduinoKwad3-GY91-1.8.16-M9-10 Alarms.cpp Alarms.h EEPROM.cpp EEPROM.h GPS.cpp GPS.h IMU.cpp IMU.h LCD.cpp LCD.h MultiWii.cpp MultiWii.h Output.cpp Output.h Protocol.cpp Protocol.h RX.cpp

```
692 // must be 0 for PRO_MINI / UNO (ex GPS_PRO_MINI) - GPS must be disconnected when using USB Serial
693 // note: Now a GPS can share MSP on the same port. The only constrain is to not use it simultaneously with some other GPS
694
695 // avoid using 115200 baud because with 16MHz arduino the 115200 baudrate have more than 2% speed error (57600 have 0.8% error)
696 //#define GPS_BAUD 9600 // GPS default
697 //#define GPS_BAUD 38400
698 #define GPS_BAUD 57600 // GPS_BAUD will override SERIALx_COM_SPEED for the selected port
699 //#define GPS_BAUD 115200
700
701 /* GPS protocol
702 NMEA - Standard NMEA protocol GGA, GSA and RMC sentences are needed
703 UBLOX - U-Blox binary protocol, use the ublox config file (u-blox-config.ublox.txt) from the source tree
704 MTK_BINARY16 and MTK_BINARY19 - MTK3329 chipset based GPS with DIYDrones binary firmware (v1.6 or v1.9)
705 With UBLOX and MTK_BINARY you don't have to use GPS_FILTERING in multiwii code !!!
706
707 SEE UCENTER https://www.u-blox.com/en/product/u-center */
708
709
710 //#define NMEA //for Ublox NMEA GPS - NMEA Protocol Pls. sea GPS.h M5-M6 Protocol M8-M10 Protocol uncomment
711 #define UBLOX //for Beitian GPS - UBLX Protocol
712 //#define MTK_BINARY16
713 //#define MTK_BINARY19
714 //#define INIT_MTK_GPS // initialize MTK GPS for using selected speed, 5Hz update rate and GGA & RMC sentence of binary settings
715
716
717 /* I2C GPS device made with an independant arduino + GPS device
718 including some navigation functions
719 contribution from EOSBandi http://code.google.com/p/i2c-gps-nav/
720 You have to use at least I2CGpsNav code r33 */
721 /* all fonctionnalities allowed by SERIAL_GPS are now available for I2C_GPS: all relevant navigation computations are gathered in the main FC */
722
723 //#define I2C_GPS
```

< >

711

Arduino/Genuino Mega or Mega 2560, ATmega2560 (Mega 2560) on COM83

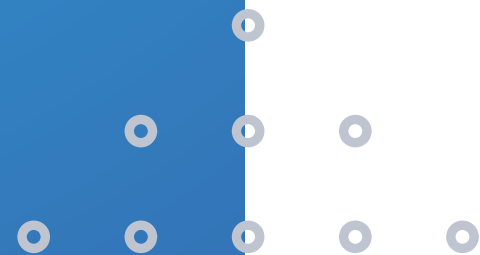
Depending on the GPS Version

Older formats uses NMEA protocol

Newer GPS uses UBLOX UBX Protocol

Support :
M6-M8 UBLOX
M8-M10 NMEA (Flash Required)

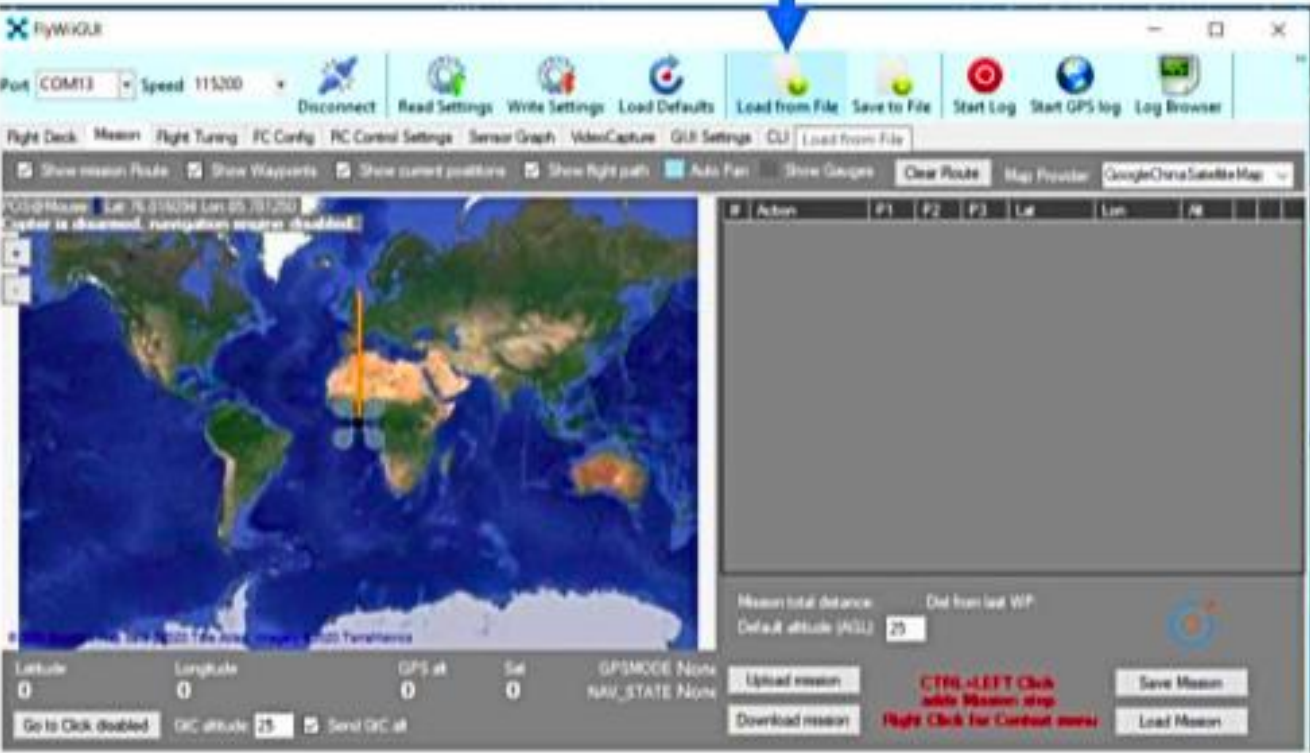
FLIGHT TUNING



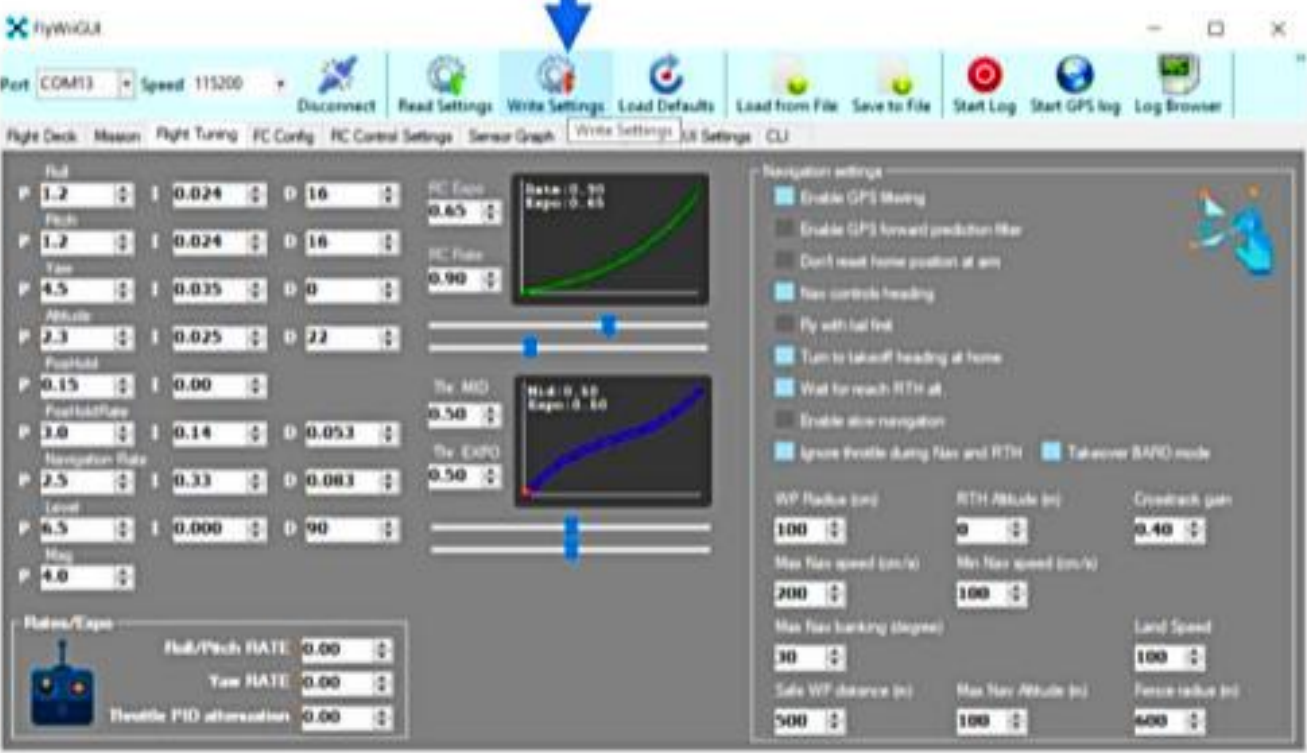
PID PARAMETERS

Download PID Parameters Preset Unzip and Load the PID file and Write settings after changes made in any of the parameters

Load the PID file



Write PID Parameter to drone



PID Parameters Preset*

PID 250mm v1.1 Slow Rate*

Download



250mm v1.1 Kwad - slow rate PID.mws

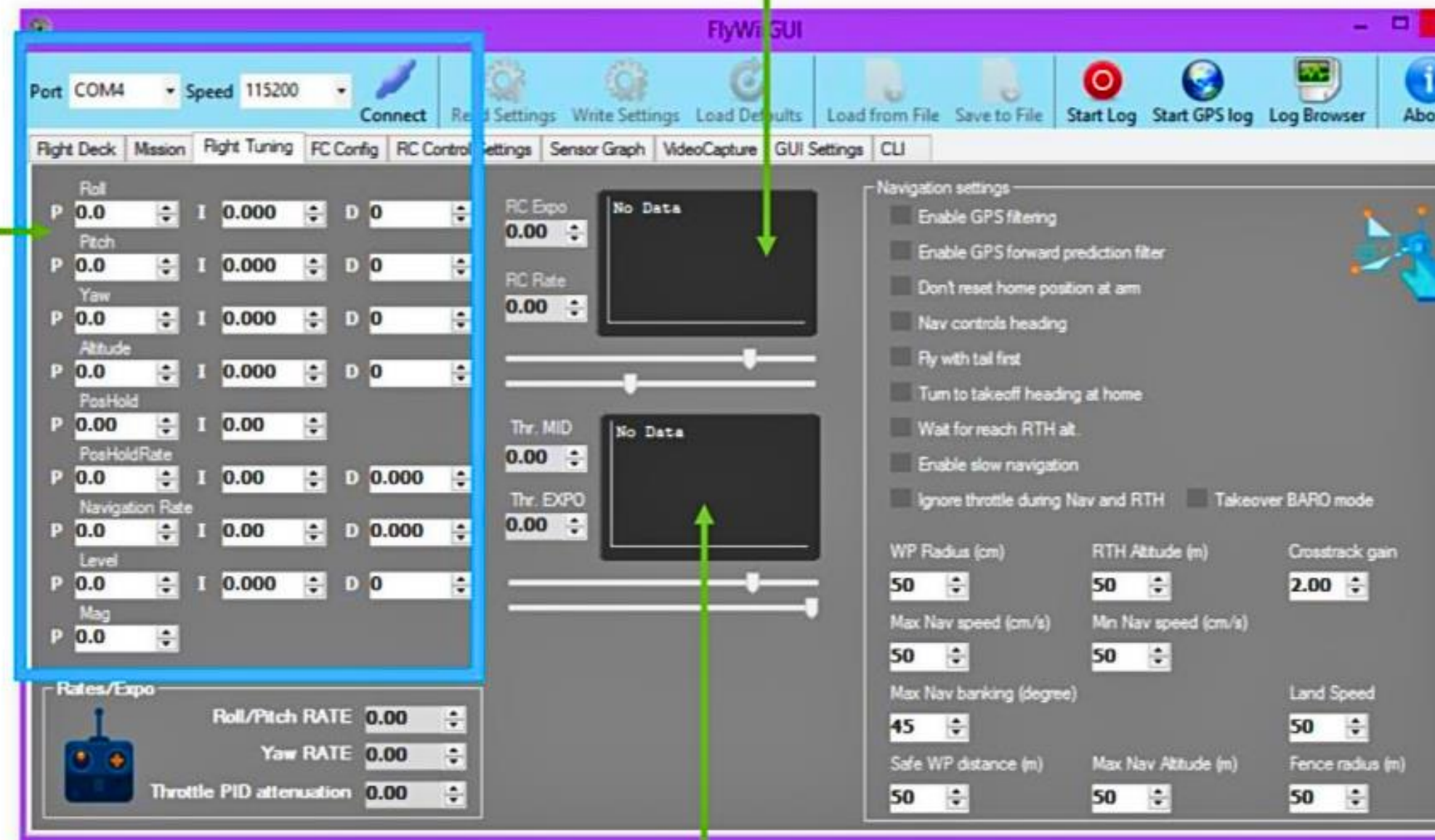
FLIGHT TUNING AND PARAMETER ADJUSTMENTS



RC RADIO EXPO RATE CONTROL , THIS CONTROL
HOW RESPONSIVE YOUR DRONE RESPOND TO
YOUR STICK INPUT

FLIGHT TUNING
FOR STABILITY
AND CONTROL
(PID)

PROPORTION
INTEGRAL
DERIVATIVE



THROTTLE CURVE EXPO THIS ALSO CONTROLS THE THROTTLE RESPONSIVENESS
AND THE DEAD ZONE FOR ALTITUDE HOLD

Understanding PID and its relation to stability and Controls

Stability	Roll,Pitch,Yaw Gyro	PID : Level of your Gyro
Horizon / Level Mode	X,Y Accelerometer	PID : X ,Y Axis Level of your Accelerometer
Heading Lock	Compass/Mag	PID : heading of your magnetometer Calibration
Altitude Hold	Barometer / Z	PID : Barometer and Z accelerometer
Position Hold	GPS Pos	PID : sensitivity of GPS position reaction
Navigation Rate	GPS Nav	

Understanding impact of P, I and D

P : this is the amount of corrective force applied to return the MultiRotor back to its initial position

The amount of force is proportional to a combination of the the deviation from initial position minus any command to change direction from the controller input. A higher P value will create a stronger force to resist any attempts to change it's position. If the P value is too high, on the return to initial position, it will overshoot and then opposite force is needed to compensate. This creates an oscillating effect until stability is eventually reached or in severe cases becomes completely destabilised.

I : this is the time period for which the angular change is sampled and averaged

The amount of force applied to return to initial position is increased by the I factor the longer the deviation exists until a maximum force value is reached. A higher I will increase the angular hold capability.

D : this is the speed at which the MultiRotor is returned to its original position

Increasing value for D: Improves the speed at which deviations are recovered

With fast recovery speed comes a higher probability of overshooting and oscillations
Will also increase the effect of P



P – proportional

P provides a proportional amount of corrective force based upon the angle of error from desired position. The larger the deviation, the larger the corrective force.

A higher P value will create a stronger force to return to desired position. If the P value is too high, on the return to initial position, it will overshoot and then opposite force is needed to compensate. This creates an oscillating effect until stability is eventually reached or in severe cases, the overshoot becomes amplified and the multi-rotor becomes completely destabilised.

Increasing value for P :It will become more solid/stable until P is too high where it starts to oscillate and lose control. You will notice a very strong resistive force to any attempts to move the Multi-Rotor

Decreasing value for P: It will start to drift in control until P is too low when it becomes very unstable. Will be less resistive to any attempts to change orientation

Aerobatic flight: Requires a slightly higher P

Gentle smooth flight: Requires a slightly lower P



I – Integral

“I” gain provides a variable amount of corrective force based upon the angle of error from desired position.

The larger the deviation and / or the longer the deviation exists, the larger the corrective force. It is limited to prevent becoming excessively high.

A higher I will increase the heading hold capability

Increasing value for I: Increase the ability to hold overall position, reduce drift due to unbalanced frames etc

Decreasing value for I: Will improve reaction to changes, but increase drift and reduce ability to hold position



D- Divide / Derivative

This moderates the speed at which the Multi-Rotor is returned to its original position.

A lower D will mean the Multi-Rotor will snap back to its initial position very quickly

Increasing value for D: Dampens changes. Slower to react to fast changes

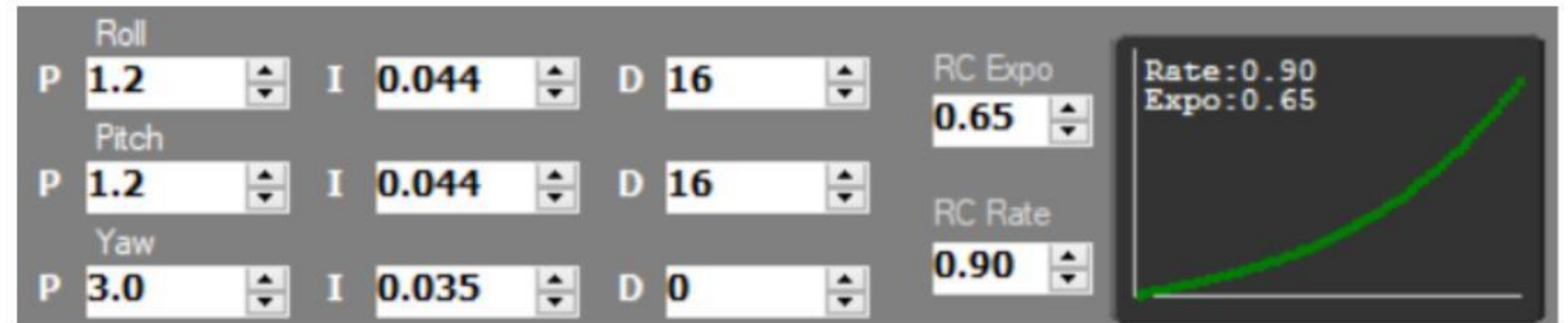
Decreasing value for D: Less dampening to changes. Reacts faster to changes

Aerobatic flight: Lower D

Gentle smooth flight: Increase D



Basic PID Tuning – on the ground



- 1 - Set PID to the designers default recommended settings.
- 2 - Hold the Multi-Rotor securely and safely in the air.
- 3 - Increase throttle to the hover point where it starts to feel light.
- 4 - Try to lean the Multi-Rotor down onto each motor axis. You should feel a reaction against your pressure for each axis.
- 5 - Change P until it is difficult to move against the reaction. Without stabilisation you will feel it allow you to move over a period of time. That is OK
- 6 - Now try rocking the Multi-Rotor. Increase P until it starts to oscillate and then reduce a touch.
- 7 - Repeat for Yaw Axis. Your settings should now be suitable for flight tuning.

ESC CALIBRATION

To ensure a
proper tune
stable flight

All ESCs must
be Calibrated

SynerduinoKwad3-GY91-1.8.16-M9-10 - config.h | Arduino 1.8.18

File Edit Sketch Tools Help

SynerduinoKwad3-GY91-1.8.16-M9-10 Alarms.cpp Alarms.h EEPROM.cpp EEPROM.h GPS.cpp GPS.h IMU.cpp IMU.h LCD.cpp LCD.h MultiWii.cpp MultiWii.h Output.cpp Output.h Protocol.cpp Protocol.h RX.cpp R

```
1163
1164
1165 /*****
1166 /****          ESCs calibration          ****/
1167 /****
1168
1169  /* to calibrate all ESCs connected to Mwii at the same time (useful to avoid unplugging/re-plugging each ESC)
1170     Warning: this creates a special version of MultiWii Code
1171     You cannot fly with this special version. It is only to be used for calibrating ESCs
1172     Read How To at http://code.google.com/p/multiwii/wiki/ESCsCalibration */
1173 #define ESC_CALIB_LOW  MINCOMMAND
1174 #define ESC_CALIB_HIGH 2000
1175 // #define ESC_CALIB_CANNOT_FLY // uncomment to activate
1176
1177 /****          internal frequencies          ****/
1178 /* frequenies for rare cyclic actions in the main loop, depend on cycle time
1179    time base is main loop cycle time - a value of 6 means to trigger the action every 6th run through the main loop
1180    example: with cycle time of approx 3ms, do action every 6*3ms=18ms
1181    value must be [1; 65535] */
1182 #define LCD_TELEMETRY_FREQ 23 // to send telemetry data over serial 23 <=> 60ms <=> 16Hz (only sending interlaced, so 8Hz update rate)
1183 #define LCD_TELEMETRY_AUTO_FREQ 967 // to step to next telemetry page 967 <=> 3s
1184 #define PSENSOR_SMOOTH 16 // len of averaging vector for smoothing the PSENSOR readings; should be power of 2; set to 1 to disable
1185 #define VBAT_SMOOTH 16 // len of averaging vector for smoothing the VBAT readings; should be power of 2; set to 1 to disable
1186 #define RSSI_SMOOTH 16 // len of averaging vector for smoothing the RSSI readings; should be power of 2; set to 1 to disable
1187
1188 /*****
1189 /****          Dynamic Motor/Prop Balancing          ****/
1190 /****
1191 /*          !!! No Fly Mode !!!          */
1192
1193 // #define DYNBALANCE // (**) Dynamic balancing controlled from Gui
1194
```

1175 - 1176

Arduino/Genuino Mega or Mega 2560, ATmega2560 (Mega 2560) on COM83

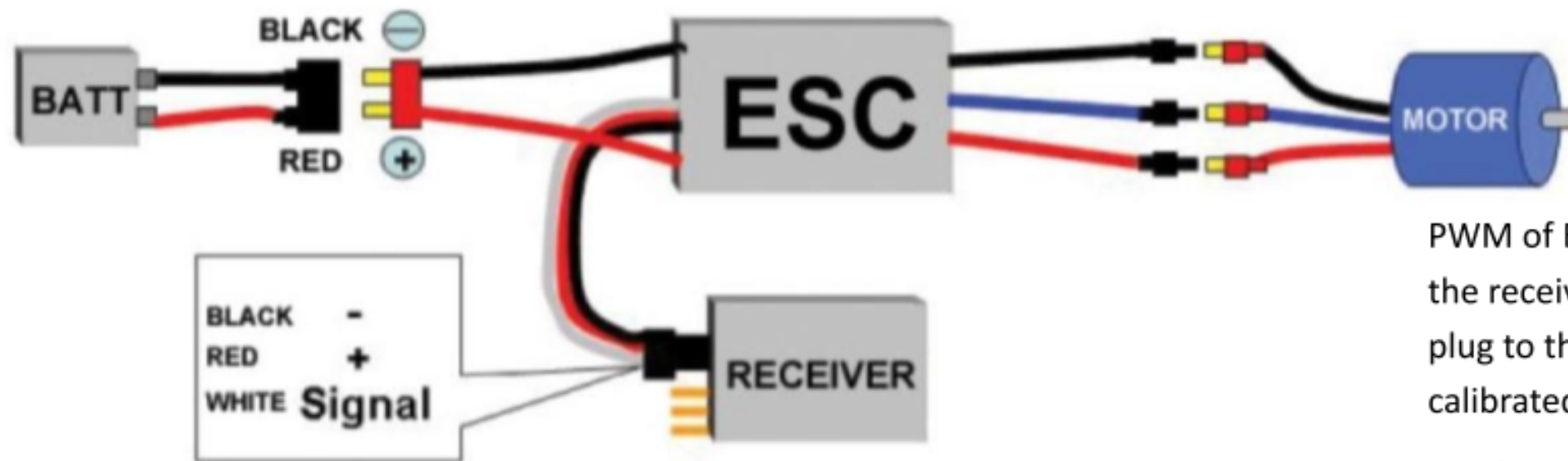
STEP

1

XLoader

Download

Electronic Speed Controller CALIBRATION



Propellers are removed during this process

ESC calibration will vary based on what brand of ESC you are using, so always refer to the documentation for the brand of ESC you are using for specific information (such as tones). “All at once” calibration works well for most ESCs, so it is good idea to attempt it first and if that fails try the “Manual ESC-by-ESC” method.

If your ESC happens to be an OPTO. The Synerduino board can provide as power supply for both RC Receiver and ESCs when soldered in . Get the PWM Pin of the ESC you want to calibrate and plug it into the Throttle Channel of your Receiver

PWM of ESC is directly hook up to the receiver Throttle pin . Ensure the receiver is getting power thru the Aux PWM pin which remains plug to the synerduino board (process is repeated till all ESCs are calibrated)

Multirotors must have all ESCs calibrated similarly to ensure reliable operations

Motor must be plug in at this point w/o the propeller. As it will serve several purpose

- An Speaker to listen to calibration tone of the ESC
- Identify motor rotation should it needs to be corrected
- Test full speed range

ESC CALIBRATION

CONFIG.H

STEP

2

Synerduino Multiwii ESC calibration method , for All ESC at Once

Throttle Pin is Connected to the Throttle Channel of the Receiver

All other Channels as is

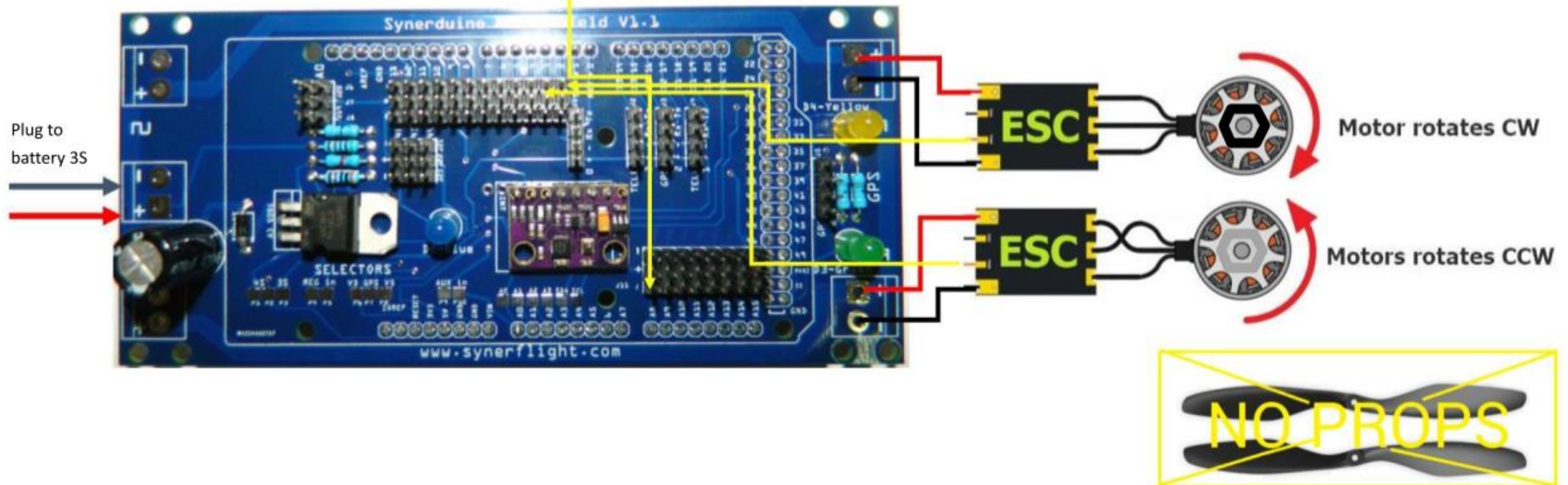


to calibrate all ESCs connected to MWii at the same time (useful to avoid unplugging/re-plugging each ESC)

Warning: this creates a special version of MultiWii Code

You cannot fly with this special version. It is only to be used for calibrating ESCs

This is applicable to those who have PPM and SBUS Receivers



STEP

4

- Remove props or tie the copter down.
- Plug in USB.
- Uncomment `#define ESC_CALIB_CANNOT_FLY` // uncomment to activate
- Flash firmware to Synerduino
- Disconnect the USB.
- Plug in the battery. The copter will not fly and will use ESC Tone/LEDs to indicate finished calibration (after approx. 5-10 seconds).
- Disconnect the battery.
- Plug in USB and Comment `#define ESC_CALIB_CANNOT_FLY` // uncomment to activate
- You can test carefully with your ESCs calibrated.



```

//=====
// 1. ESC Calibration
//=====
// To calibrate all ESCs connected to the main loop, upload the main loop
// firmware. This will cause a special version of the main loop
// to be uploaded to the main loop. It is only to be used for calibrating ESCs.
// Do not use this version for anything else.
//=====
// 2. ESC Calibration
//=====
// To calibrate all ESCs connected to the main loop, upload the main loop
// firmware. This will cause a special version of the main loop
// to be uploaded to the main loop. It is only to be used for calibrating ESCs.
// Do not use this version for anything else.
//=====
// 3. ESC Calibration
//=====
// To calibrate all ESCs connected to the main loop, upload the main loop
// firmware. This will cause a special version of the main loop
// to be uploaded to the main loop. It is only to be used for calibrating ESCs.
// Do not use this version for anything else.
//=====
// 4. ESC Calibration
//=====
// To calibrate all ESCs connected to the main loop, upload the main loop
// firmware. This will cause a special version of the main loop
// to be uploaded to the main loop. It is only to be used for calibrating ESCs.
// Do not use this version for anything else.
//=====

```



```

//=====
// 1. ESC Calibration
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```



FLYWIIGUI INSTALLATION

STEP

1

Download the FlyWiiGUI groundstation and open FlywiiGUI.exe

Name	Date modified	Type	Size
210130-0301	30/04/2021 3:01 PM	File	3 KB
210814-0408	14/09/2021 4:08 PM	File	3 KB
212812-0428	12/06/2021 4:28 PM	File	3 KB
214012-0340	12/06/2021 3:40 PM	File	3 KB
AForge.Controls.dll	25/01/2015 1:15 PM	Application extens...	44 KB
AForge.dll	25/01/2015 1:15 PM	Application extens...	17 KB
AForge.Imaging.dll	25/01/2015 1:15 PM	Application extens...	248 KB
AForge.Math.dll	25/01/2015 1:15 PM	Application extens...	67 KB
AForge.Video.DirectShow.dll	25/01/2015 1:15 PM	Application extens...	52 KB
AForge.Video.dll	25/01/2015 1:15 PM	Application extens...	19 KB
AForge.Video.FFMPEG.dll	25/01/2015 1:15 PM	Application extens...	60 KB
avcodec-53.dll	25/01/2015 1:15 PM	Application extens...	13,181 KB
avdevice-53.dll	25/01/2015 1:15 PM	Application extens...	342 KB
avfilter-2.dll	25/01/2015 1:15 PM	Application extens...	870 KB
avformat-53.dll	25/01/2015 1:15 PM	Application extens...	2,405 KB
avutil-51.dll	25/01/2015 1:15 PM	Application extens...	135 KB
 FlyWiiGUI.exe	30/10/2021 11:41 ...	Application	6,945 KB
FlyWiiGUI.exe.config	28/02/2017 5:31 PM	CONFIG File	1 KB
FlyWiiGUI.exe.manifest	30/10/2021 11:41 ...	MANIFEST File	30 KB

The FlyWii GUI is a free updated version of the [MultiWii WinGUI](#). It serves as the ground control station for the MultiWii 2.4 controller software.

FlyWii GUI is currently only supported for Windows 7/8/10



Download

Latest Release

FlwiiGUI Ground Station Software .EXE*

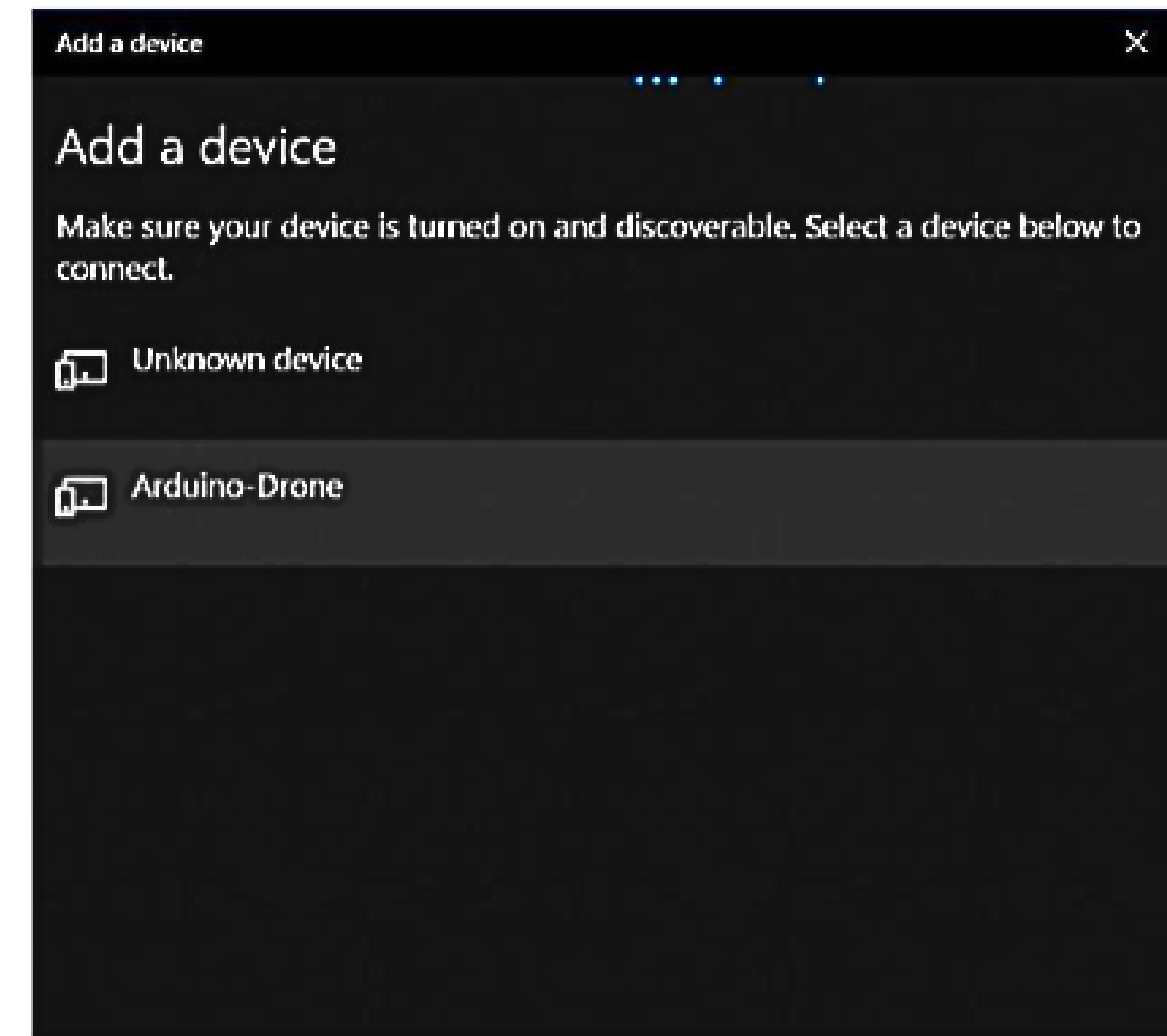
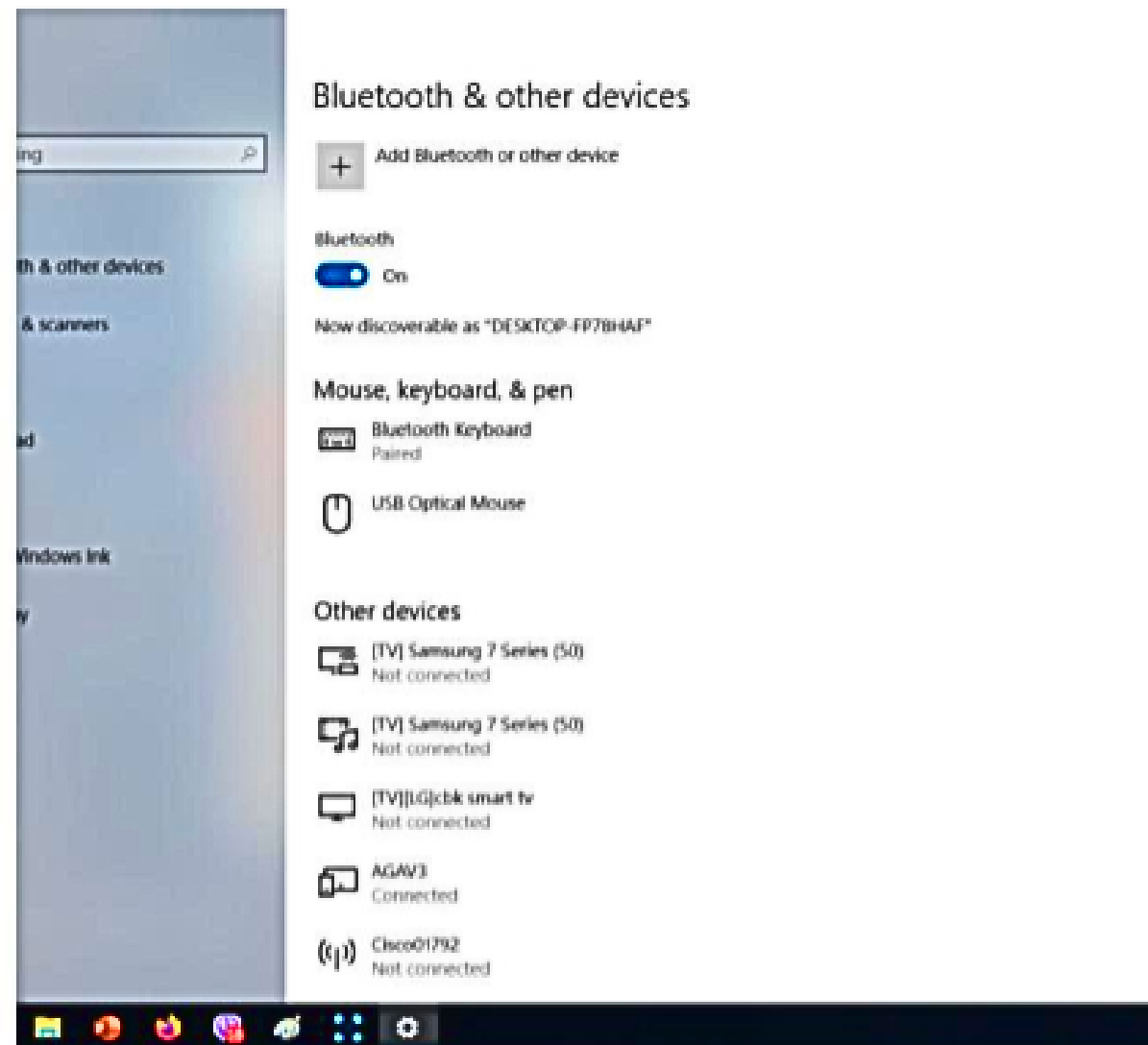
FlyWiiGUI20

Download

FLYWIIGUI INSTALLATION

STEP

2



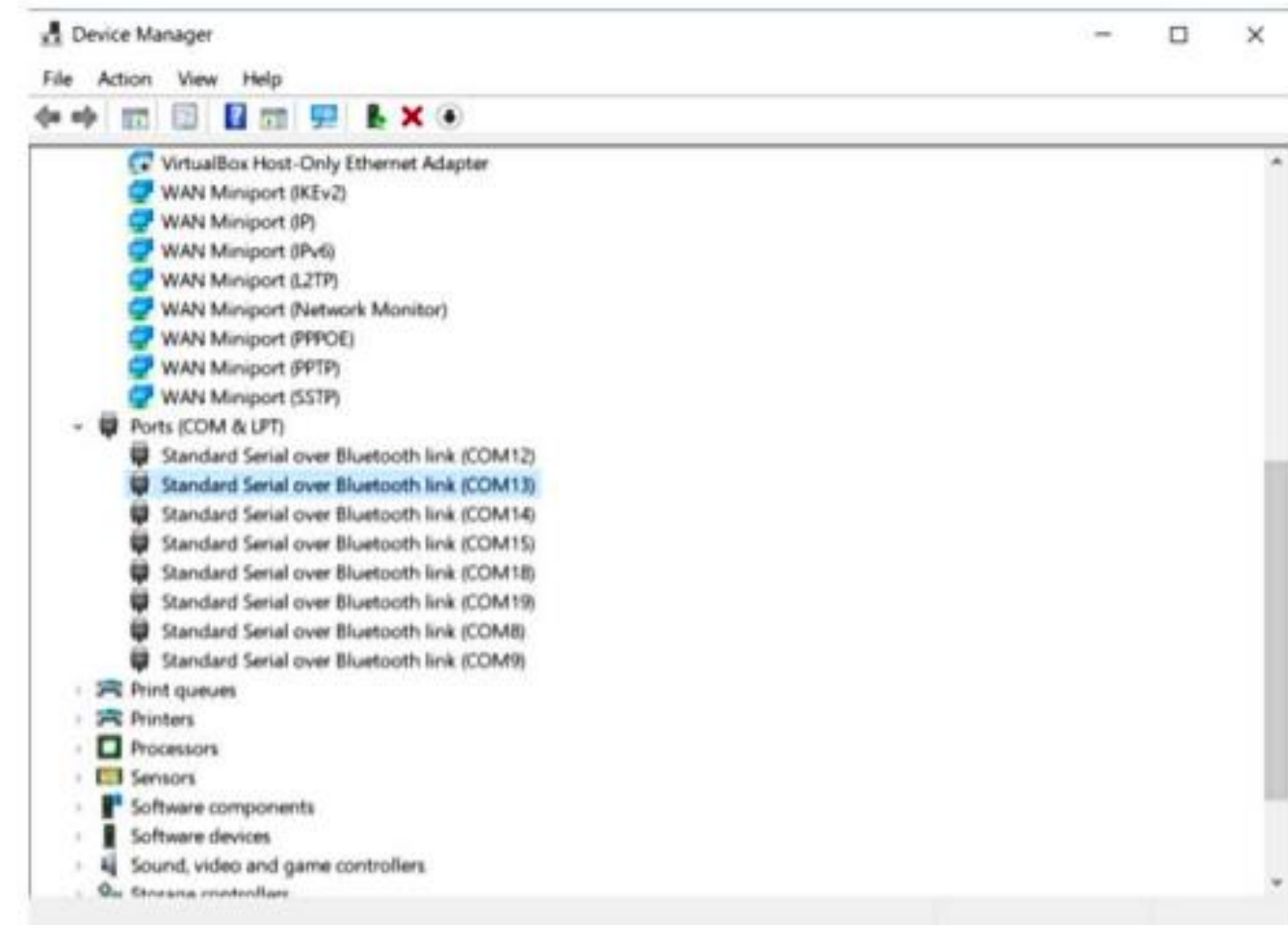
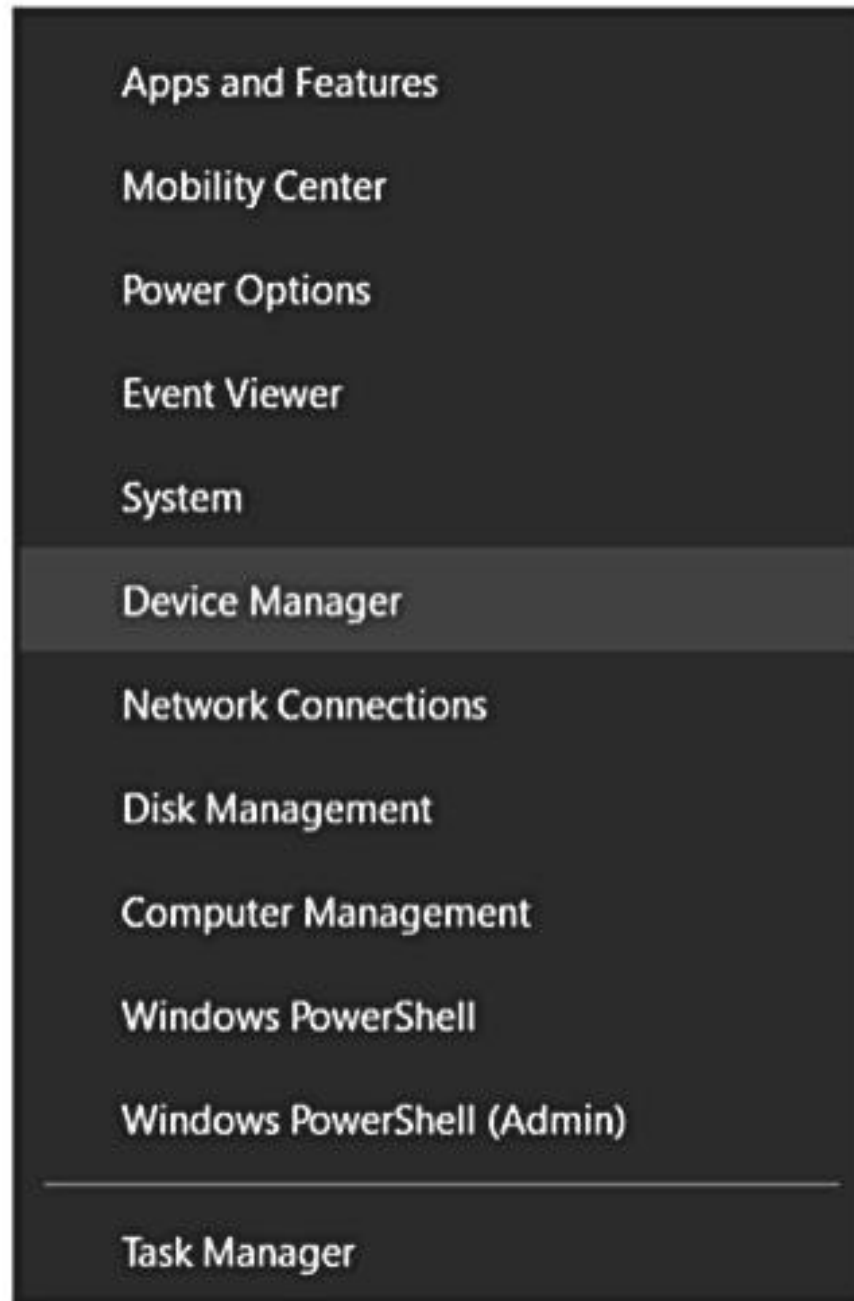
Adding Bluetooth on Windows Device Manager look for Arduino-Drone BT device

Take note on which Serial Com port its added to in Device Manager

FLYWIIGUI INSTALLATION

STEP

3



In Device Manager Located in COM & LPT

FLYWIIGUI INSTALLATION

STEP

4

Select the com port your Bluetooth is connected to .

At this point Disconnect your Physical USB and your drone should be running on batteries using only the Bluetooth to communicate

Connect to the Drone with the associated COM port and Baud as found in your device manager



FLYWIIGUI INSTALLATION

Calibration Acc – Drone must be on level surface

Write settings after changes made in any of the parameters

Serial Com

Altitude

Heading

Calibration Mag/Compass

Flight Log

RC PWM

Refresh rate

Attitude

GPS

Serial Data

Vertical Speed

Analog sensor / Battery

Sensor Status

Frame type / Motor PWM

The screenshot shows the FlyWiigUI software interface. At the top, there is a menu bar with options: Connect, Read Settings, Write Settings, Load Defaults, Load from File, Save to File, Start Log, Start GPS log, Log Browser, and About. Below the menu bar is a toolbar with buttons: Refresh Rate, Pause, Calibrate ACC, Calibrate Mag, and Bind Spektrum. The main display area contains several circular gauges and a central display. The gauges include: a compass showing heading (labeled 'Heading'), a vertical speed gauge (labeled 'Vertical Speed'), a GPS gauge showing distance to home (labeled 'GPS'), an attitude gauge (labeled 'Attitude'), a speed gauge (labeled 'Speed 11520'), and an altitude gauge (labeled 'Altitude'). The central display shows a quadcopter icon and a battery voltage gauge (labeled 'Analog sensor / Battery'). To the right of the gauges is a section for 'Active Sensors' with buttons for ACC, GPS, BARO, MAG, OPTIC, and SONAR. Below this is a table for 'RC PWM' settings, listing parameters like Thr, Pitch, Roll, Yaw, and Aux1 through Aux8, each with a corresponding value. At the bottom right, there is a 'Sensor Status' section showing PC Error count, Battery Voltage, and Power Sum. Arrows from the labels point to the corresponding elements in the interface.

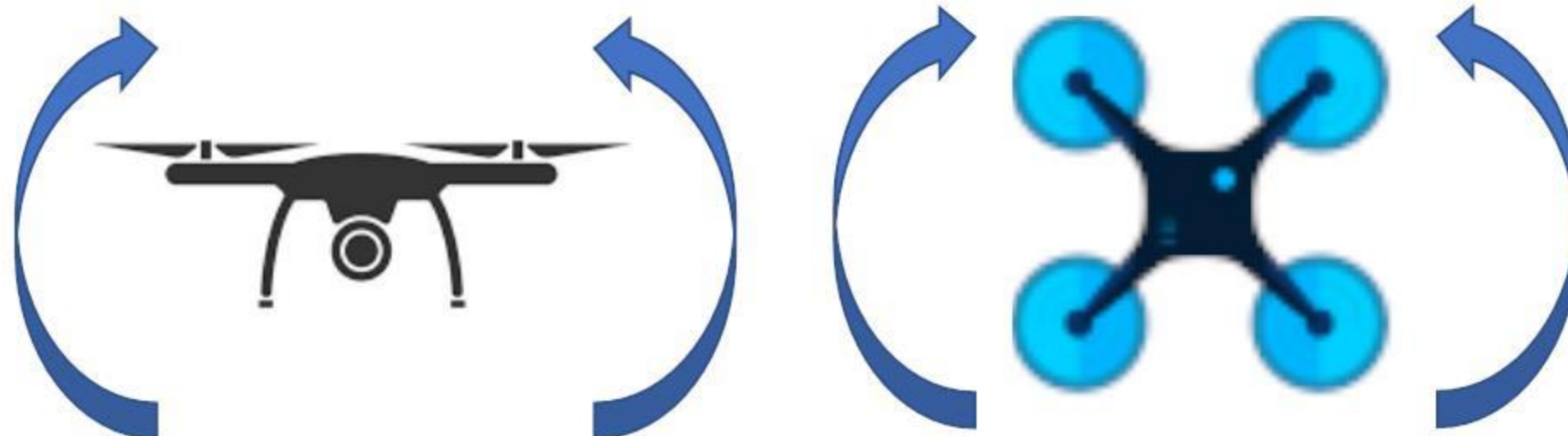


You will have to accept a compromise of optimal settings for stable hover and your typical mode of flying.

Obviously factor it towards your most common style.

Other factors affecting PID Taking known good PID values from an identical configuration will get you close, but bear in mind no two Multi-Rotors will have the same flying characteristics and the following items will have an impact on actual PID values:

- 1 - Frame weight /size / material / stiffness
- 2 - Motors - power / torque /momentum
- 3 - Position - Motor-->motor distance (I.E. frame size)
- 4 -ESC / TX - power curves
- 5 - Prop - diameter / pitch / material
- 6 - BALANCING
- 7 - Pilot skills





Advanced Tuning - practical implementation

For Aerobatic flying: Increase value for P until oscillations start, then back of slightly

Change value for I until wobble is unacceptable, then decrease slightly

Decrease value for D until recovery from dramatic control changes results in unacceptable recovery oscillations, then increase D slightly Repeat above steps

For stable flying (RC): Increase value for P until oscillations start, then back of quite a bit

Decrease value for I until it feels too loose /unstable then increase slightly
Increase value for D



PID : Level

Level		
P	8.0	I
	0.002	D
	80	

This will influence the flight characteristic with an accelerometer : this is Level Mode

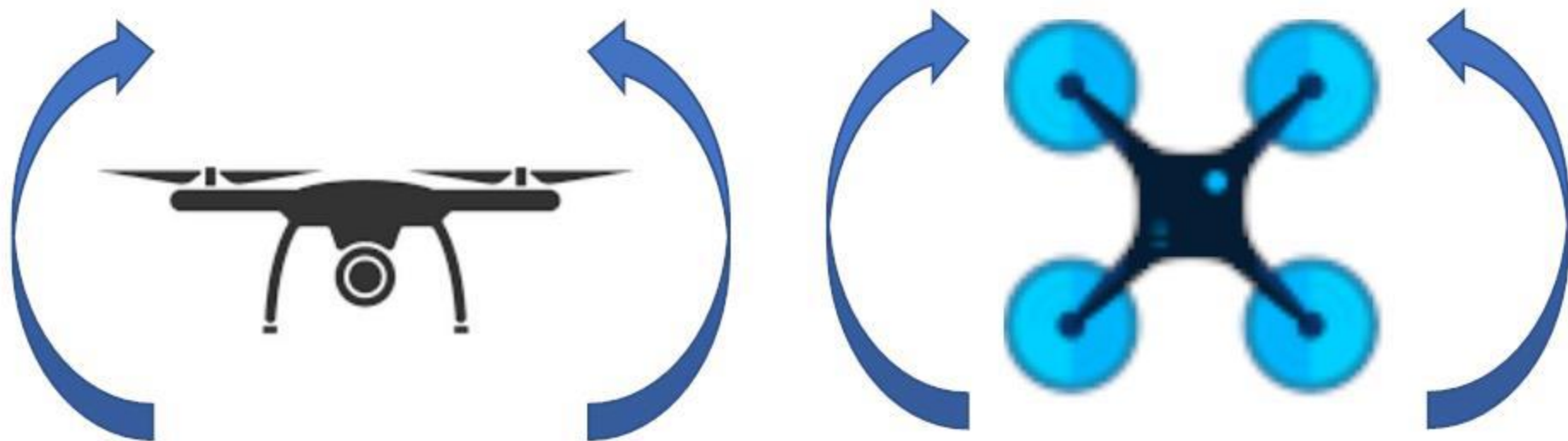
P is the dominant part of autolevel mode.

I will tell how much force must be applied when the measured angle error persit

D is used to clamp the maximum correction for autolevel mode

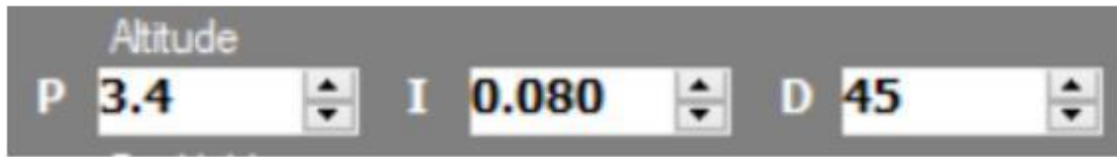
Increase value for P will make the autolevel mode stronger

For smooth operation the sum of P axis + P level should stay near the default value : if you decrease P for Roll and Pitch axis you can increase P Level





ALT Hold



The Barometer sensor is used to detect the altitude of your multirotor aircraft and is used for altitude hold mode. As the barometer sensor is not very precise and is quite noisy, detection of small up and down movements is impossible.

So small up and down movements are detected by the accelerometer Z axis.

Combination of these two sensors gives good altitude hold.

PID settings for ALT works like this:

P - Is how much the multirotor should rely on the barometer sensor. The higher the value is the stronger the multirotor relies on the Barometer reading.

I - Is used to compensate for drift caused by battery voltage drop during the flight. The higher the value is more the multirotor will react to voltage drops (or other varying factors over time).

D - Is how strong the multirotor should react to data from the accelerometer Z axis. It is used to react to small up and down movements that the barometer cannot accurately sense. The higher the value is the stronger the multirotor will react to small altitude changes.





1. So set the P and I to 0
2. Start to play with D value only. Too high D may cause yoyo effect (up and down oscillations). With too low D the copter will be not able to react strong/fast enough to hold altitude. Your goal here is to set D to the value when copter doesn't oscillate up and down and also holds altitude quite well for a not very long period of time. Copter will not hold altitude perfectly at this point during long periods. It will slowly drift up or down, but altitude should be quite stable in short periods.
3. Start to increase P to the point where copter holds altitude over long time period. If the value is too small the copter will drift slowly up and down. If the value is too high yoyo effect may appear. Goal here is to set it to the point where copter holds altitude for quite some time. Copter will still go slowly down due to battery voltage drop over time.
4. "I" is used to compensate the voltage drop. So start to increase the "I" value slowly until you get a perfect position hold during a very long time.
Now your altitude hold should be good enough.

For Mega 2560 + GPS Pos Rate PID controller & Pos Rate PID Tuning

Pos Rate PID controller

Pos Rate PID Tuning

The Pos Rate PID controller takes the commanded speed output from the Pos PI controller and commands an attitude in order to maintain the position hold location. This PID controller should be tuned before adjusting the Pos PI controller.

The Pos Rate PID settings control how the attitude of the multirotor is changed in order to move towards the desired hold location.

The speed of movement is controlled by the Pos PI controller, while the attitude of the multirotor is controlled by Pos Rate.

When the multirotor is within the defined distance of the hold location or waypoint (set by GPS_WP_RADIUS in config.h) the Pos Rate PID is used, when further away from the location the Nav Rate PID is used to return to within the defined waypoint radius.

For Mega 2560 + GPS Pos Rate PID controller & Pos Rate PID Tuning

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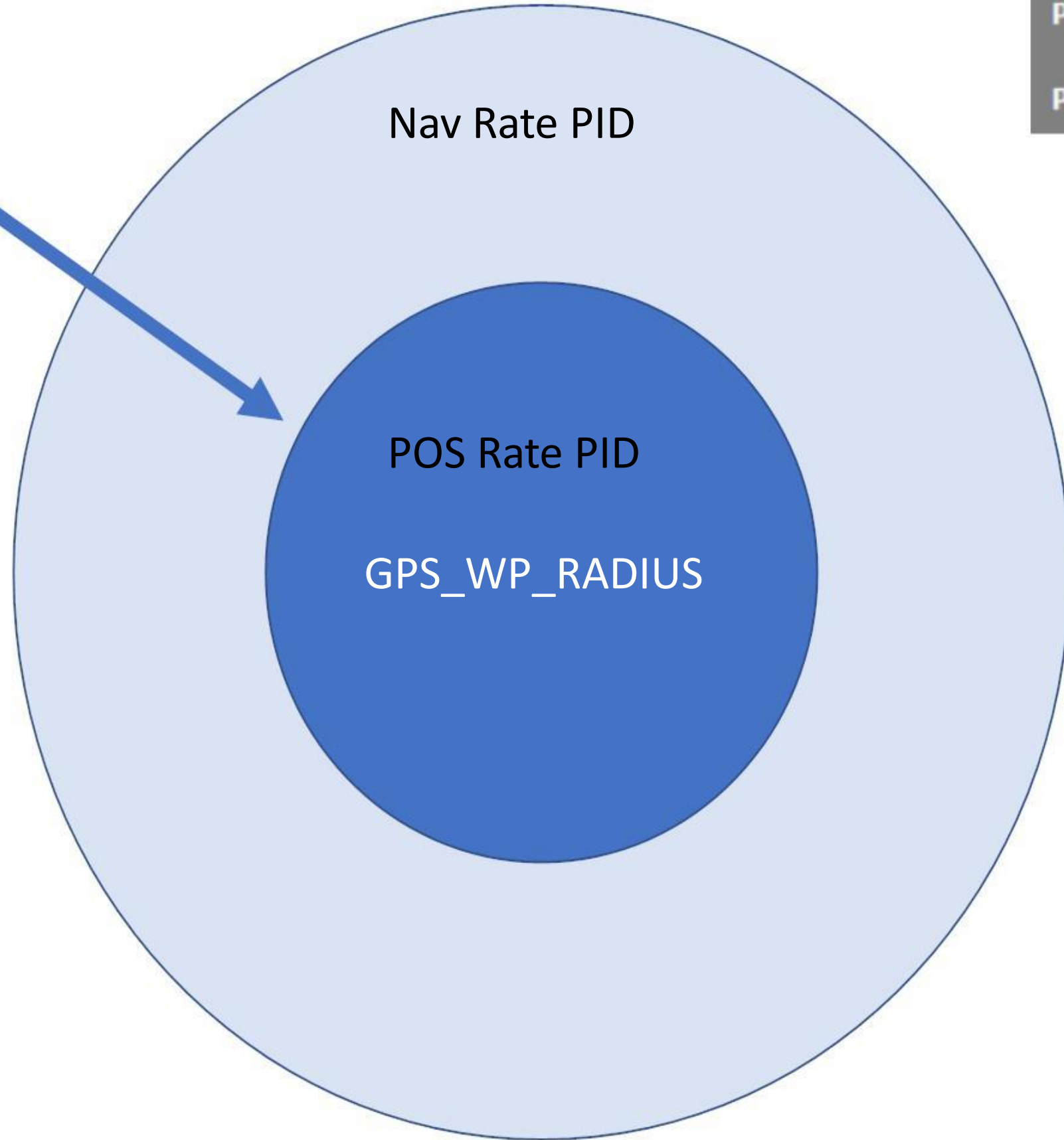
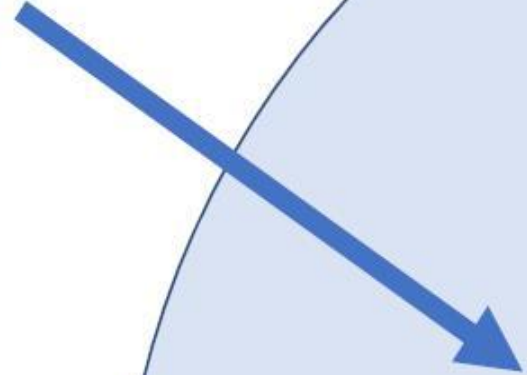
When the multirotor is within the defined distance of the hold location or waypoint (set by GPS_WP_RADIUS in config.h) the Pos Rate PID is used, when further away from the location the Nav Rate PID is used to return to within the defined waypoint radius.

To tune the Pos Rate PID, initially set P, I and D values to 0.

Gradually increase P until the multirotor begins to position hold with some drift.

Gradually increase D until the multirotor responds more quickly to undesired changes in attitude caused by the wind. If this value is set too high you will see oscillations or sudden jerking in pitch and roll motion.

If needed, gradually increase I value to allow the PID controller to compensate for long lasting error, ie if it is being blown by the wind.



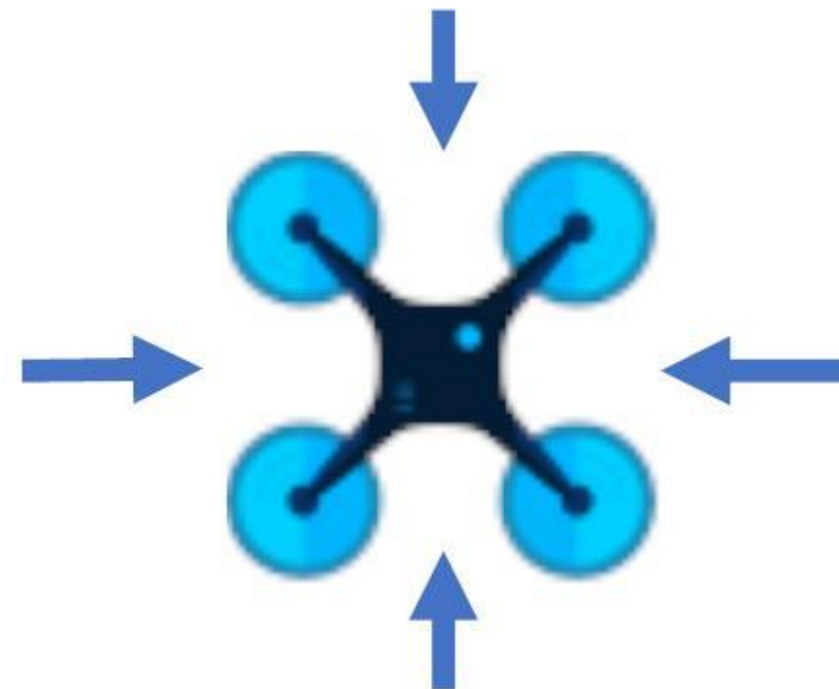
PosHold					
P	0.15		I	0.00	
PosHoldRate					
P	3.4		I	0.14	D 0.053
Navigation Rate					
P	2.5		I	0.33	D 0.083

To tune the Pos Rate PID, initially set P, I and D values to 0.

Gradually increase P until the multirotor begins to position hold with some drift.

Gradually increase D until the multirotor responds more quickly to undesired changes in attitude caused by the wind. If this value is set too high you will see oscillations or sudden jerking in pitch and roll motion.

If needed, gradually increase I value to allow the PID controller to compensate for long lasting error, ie if it is being blown by the wind.



FLIGHT TUNING AND PARAMETER ADJUSTMENTS

On Flight Deck Tab calibrate your drone

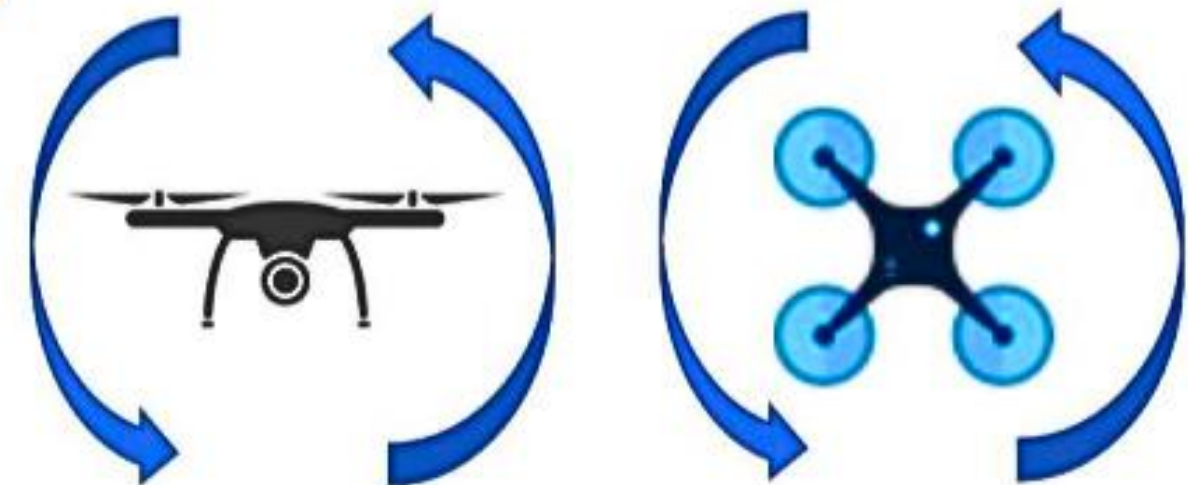


Refresh Rate . Telemetry update speed

Acc Calibration . Set the drone down on a level surface . Away from any metal objects for 30 secs.

Mag Calibration . Move the drone 360 degrees in all axis within 1 min. while the blue Led flashes

These Calibration must be perform after Parameter updates after Flashing the firmware



FLIGHT TUNING AND PARAMETER ADJUSTMENTS



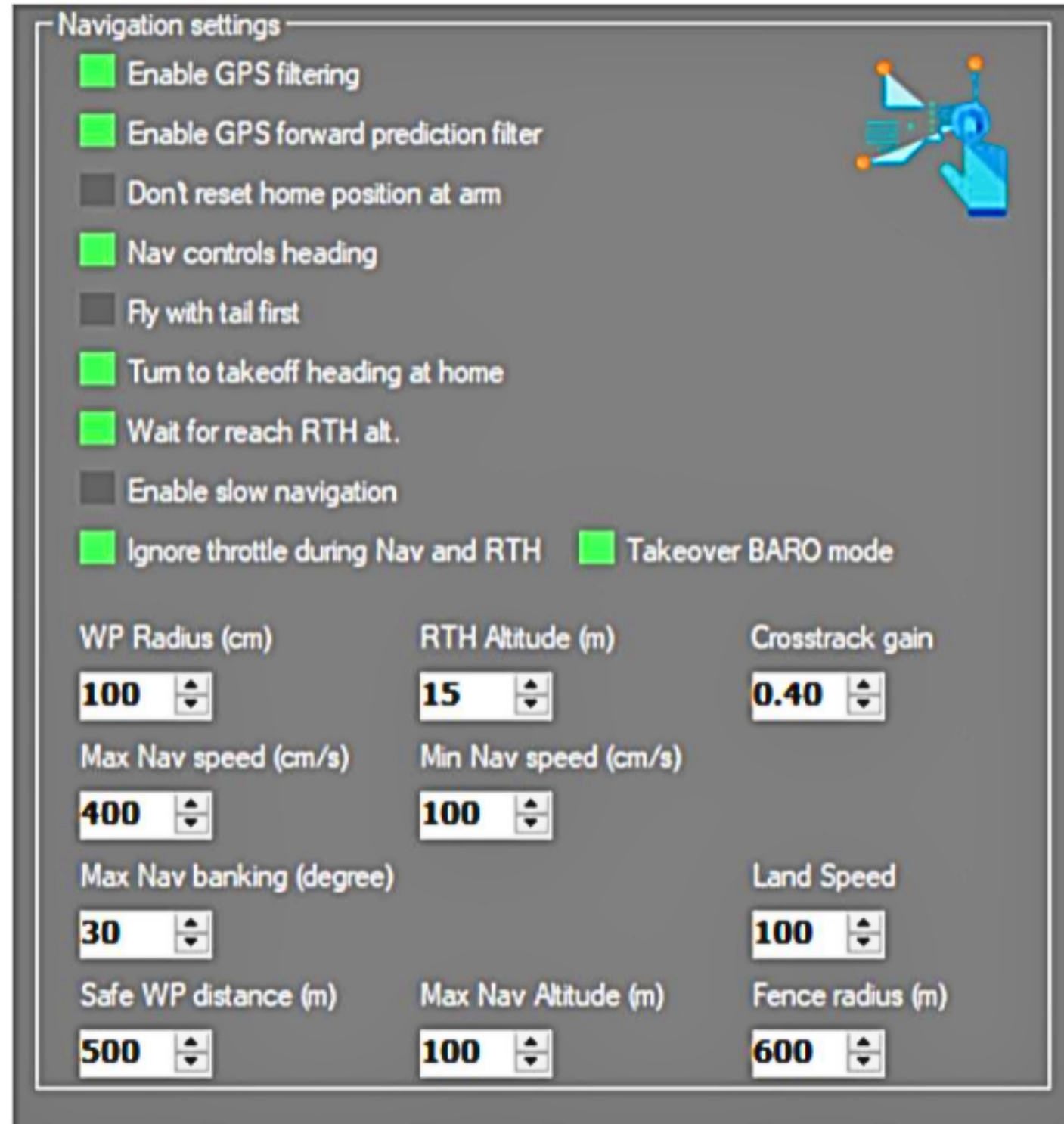
Graphs and Data Logging



Check the Graphs to ensure each sensors are correctly oriented properly

FLIGHT TUNING AND PARAMETER ADJUSTMENTS

Other Navigation Functions



Navigation settings

- ☒ Enable GPS filtering
- ☒ Enable GPS forward prediction filter
- ☐ Don't reset home position at arm
- ☒ Nav controls heading
- ☐ Fly with tail first
- ☒ Turn to takeoff heading at home
- ☒ Wait for reach RTH alt.
- ☐ Enable slow navigation
- ☒ Ignore throttle during Nav and RTH
- ☒ Takeover BARO mode

WP Radius (cm): 100

RTH Altitude (m): 15

Crosstrack gain: 0.40

Max Nav speed (cm/s): 400

Min Nav speed (cm/s): 100

Max Nav banking (degree): 30

Land Speed: 100

Safe WP distance (m): 500

Max Nav Altitude (m): 100

Fence radius (m): 600

WP Radius – the radius of the area the Pos PID with trigger it has reach the waypoint

Max Nav Speed – Maximum speed the drone travel between waypoints (too fast and you likely over shoot your target) *for first mission flight test Nav speed of 100cm/s with ("Enable Slow Navigation "Active)*

Min Nav Speed – the speed the drone travel when with in the WP Radius

RTH Altitude – Altitude the drone will climb to when its below the altitude in relation to its home point when the RTH is trigger set this to 0 to RTH at current altitude

Max Nav Banking – the max allowable pitch and roll the drone will be set too while traveling between waypoints (tune this along with Max Nav Speed to take account with Environment conditions)

Max Nav Altitude – Max altitude the drone is cap to fly at

Land Speed – speed of descending for Landing cm/s

Safe WP Distance – max distance between waypoint before its null out

Fence Radius – Geo Fence to keep the drone with in the perimeter in relation to home position

CrossTrack gain - this tune the GPS and Nav sensitivity

GPS Filtering – use to enhance GPS accuracy

GPS Forward Prediction Filter – predicting the drones location and to compensate for lag . (optional) – not necessary for most application

FLIGHT TUNING AND PARAMETER ADJUSTMENTS

Navigation settings

☒ Enable GPS filtering

☒ Enable GPS forward prediction filter

☐ Don't reset home position at arm

☒ Nav controls heading

☐ Fly with tail first

☒ Turn to takeoff heading at home

☒ Wait for reach RTH alt.

☐ Enable slow navigation

☒ Ignore throttle during Nav and RTH

☒ Takeover BARO mode

WP Radius (cm)

RTH Altitude (m)

Crosstrack gain

Max Nav speed (cm/s)

Min Nav speed (cm/s)

Max Nav banking (degree)

Land Speed

Safe WP distance (m)

Max Nav Altitude (m)

Fence radius (m)



Don't Reset Home position at Arm – this retains the home position where you first plug power on your drone

Nav Controls Heading – this points the drone to its next waypoint

Fly tail first – makes the drone fly reverse (don't use unless it's a camera pull out shot)

Turn take off heading at Home – when drone arrives at home position it orientates to its heading right after arming

Wait to reach RTH - this works with RTH altitude command which the drone would climb to the said altitude before initiating the flight to home position

Enable slow navigation – this works with keeping the drone to its **Min Nav speed**

Ignore throttle and Take over Baro – as the name suggest disable throttle stick command from the controller when the drone is on mission mode

FLIGHT TUNING AND PARAMETER ADJUSTMENTS

FlyWiiGUI

Port COM17 Speed 115200

Disconnect Read Settings Write Settings Load Defaults

Flight Deck Mission Flight Tuning FC Config RC Control Settings Sensor Graph VideoCapture GUI Settings

Roll
P 1.2 I 0.024 D 16
Pitch
P 1.2 I 0.024 D 16
Yaw
P 4.5 I 0.035 D 0
Altitude
P 2.8 I 0.010 D 15
PosHold
P 0.15 I 0.00
PosHoldRate
P 3.0 I 0.14 D 0.053
Navigation Rate
P 3.0 I 0.33 D 0.083
Level
P 6.5 I 0.000 D 90
Mag
P 4.0

RC Expo 0.65
RC Rate 0.90
Rate: 0.90
Expo: 0.65

Thr. MID 0.50
Thr. EXPO 0.50
Mid: 0.50
Expo: 0.50

Rates/Expo
Roll/Pitch RATE 0.00
Yaw RATE 0.00
Throttle PID attenuation 0.00

RC RADIO EXPO RATE CONTROL , THIS CONTROL HOW RESPONSIVE YOUR DRONE RESPOND TO YOUR STICK INPUT

HIGHER NUMBER MEANS MORE RESPONSIVENESS THE DRONE TO STICK INPUTS

FOR BEGINNERS WE RECOMMEND RC RATE AT .50-.60 THIS OFFER A MORE SLUGGISH RESPONDS OF THE DRONE AND NOT ADVICE ABLE FOR STRONG WINDS CONDITION

THROTTLE CURVE EXPO THIS ALSO CONTROLS THE THROTTLE RESPONSIVENESS AND THE DEAD ZONE FOR ALTITUDE HOLD

ADJUST THIS FOR YOUR THROTTLE RESPOND RATE AND WHERE YOUR CENTER STICK DEADBAND FOR ALTITUDE HOLD IS

FLIGHT TUNING AND PARAMETER ADJUSTMENTS

Set Flight Modes and Failsafe Modes using the Aux switch on your remote then hit the write setting icon

Write settings Parameter to drone

Flight mode Highlighted when Mode is on

The screenshot shows the FlyWiiGUI interface with the following elements:

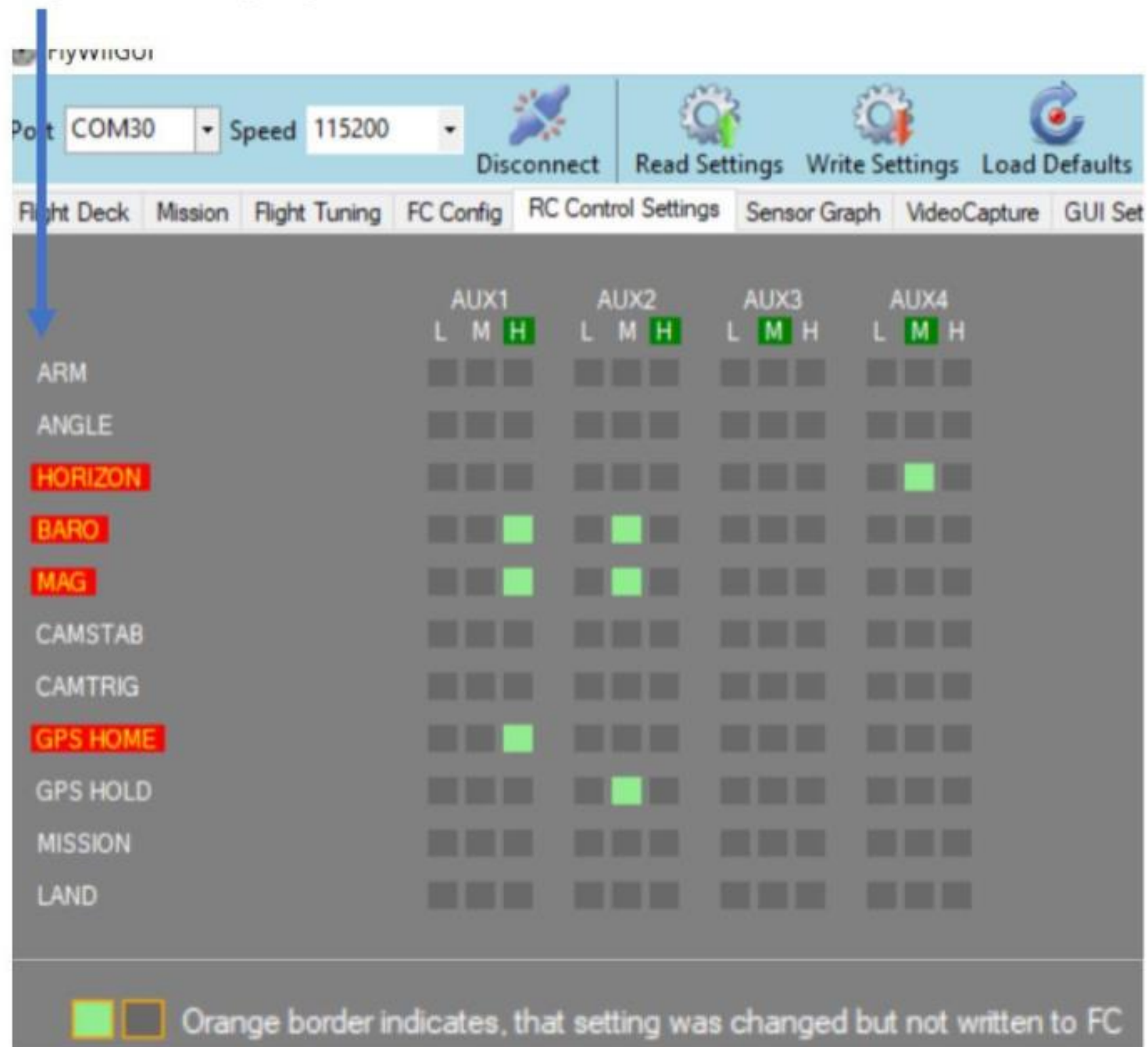
- Top Toolbar:** Includes buttons for Disconnect, Load Settings, Write Settings (highlighted), Load Defaults, Load from File, Save to File, Start Log, Start GPS log, and Log Browser.
- Left Sidebar:** Lists flight modes: ARM, ANGLE, HORIZON (highlighted with an orange border), BARO, MAG, CAMSTAB (highlighted with an orange border), CAMTRIG, GPS HOME, GPS HOLD, MISSION, and LAND.
- RC Control Settings:** A section on the right with text instructions: "Use Aux switch to setup flight modes and Navigation functions. For beginners we recommend the Horizon is Permanently active." It also lists options for ARM, BARO, MAG, HEADFREE, GPS Home, GPS Hold, and MISSION.
- Live RC data:** A panel on the far right showing status for Thr, Pitch, Roll, Yaw, and Aux1 through Aux4, each with a green bar and a value of 1500.

Orange border indicates, that setting was changed but not written to FC

For Beginners set Horizon Mode to permanently active

FLIGHT TUNING AND PARAMETER ADJUSTMENTS

Flight mode Highlighted when Mode is on



Click on the
Box to
Highlight on
position



Mode on



Mode off

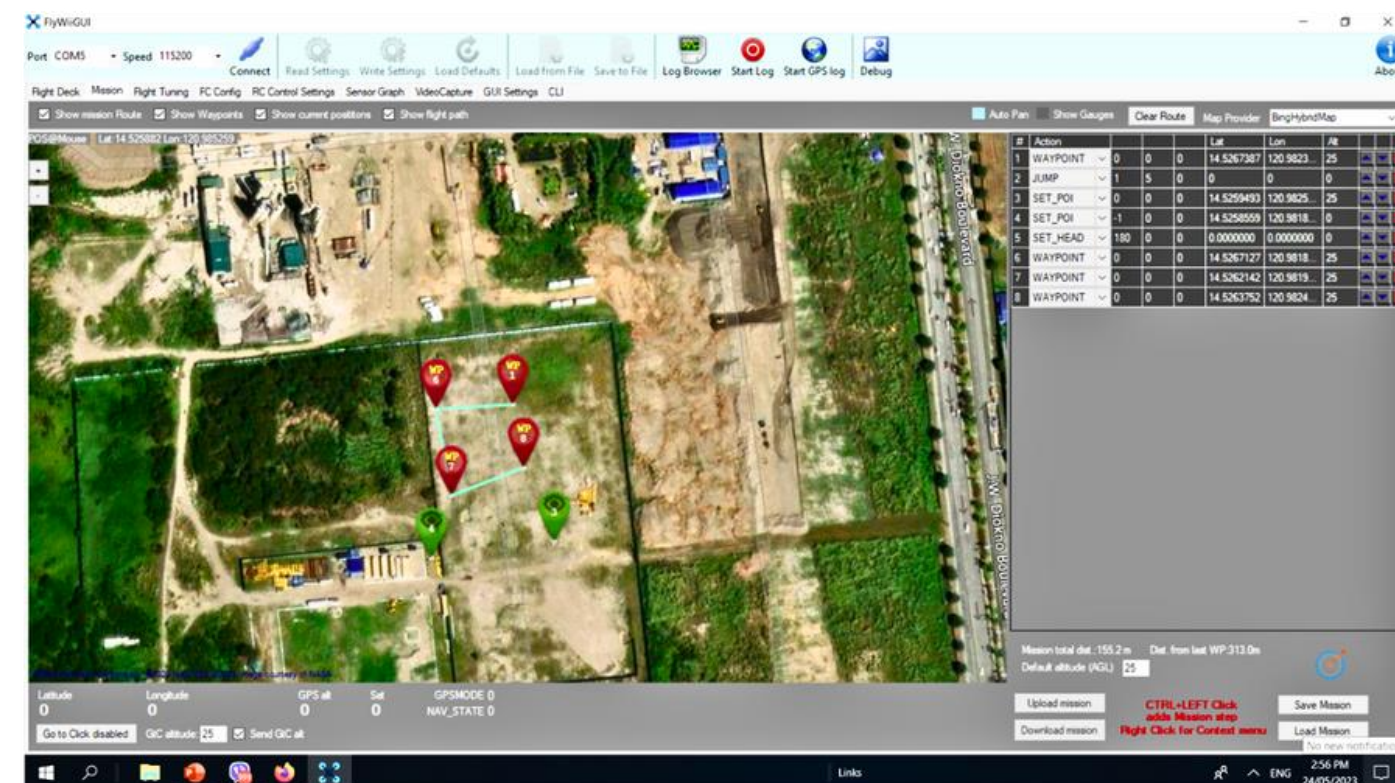
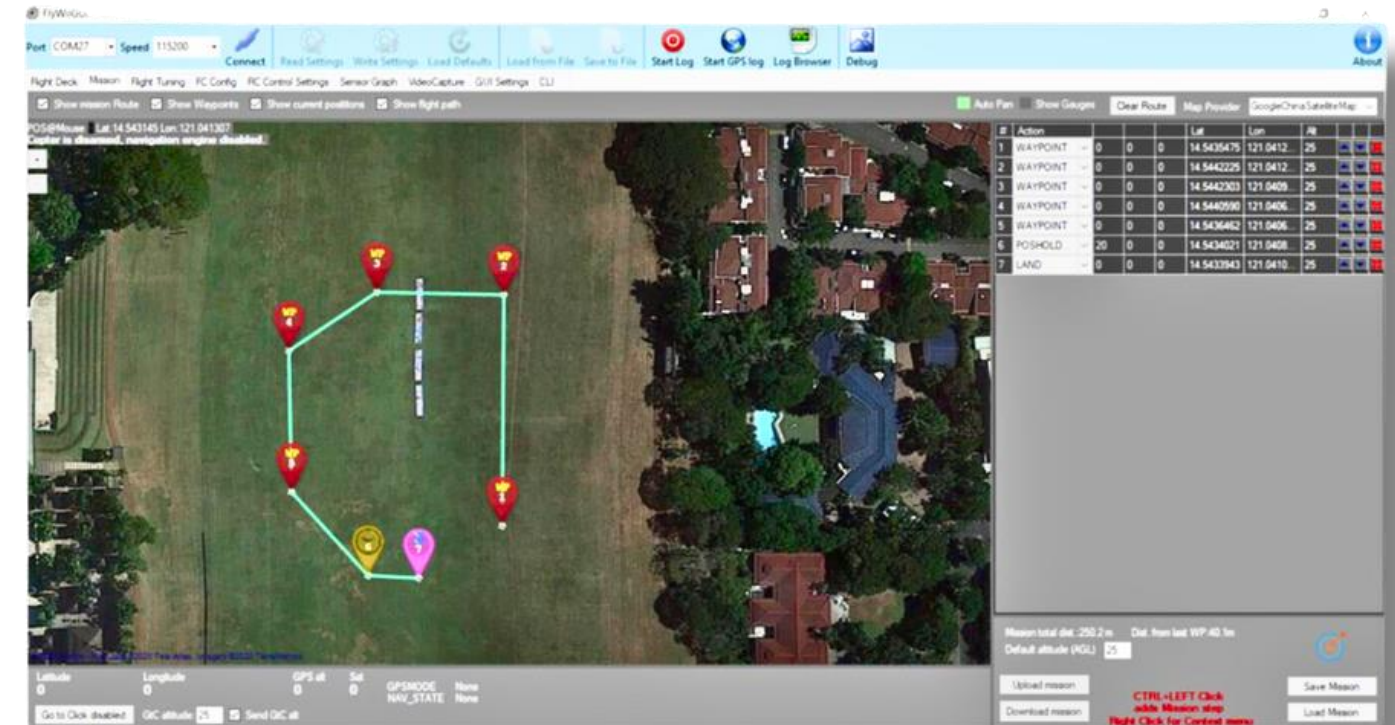
For Beginners

- **Horizon** mode is permanently active
- Other flight modes Place on switch & must be off when Arming or not in use

MISSIONS

Missions

1. Power on the UAV and ground control station.
2. Ensure that the UAV and ground control station are connected.
3. Calibrate the UAV's compass and accelerometer before flight.
4. Check the GPS signal to ensure it is stable and that the UAV has locked onto multiple satellites.
5. Plan the mission using the mission planning software:
 - Set waypoints and define actions at each waypoint.
 - Set altitude, speed, and other flight parameters.
6. Upload the mission to the UAV.
7. Arm the UAV by performing the arming procedure as defined by the flight controller.
8. Take off manually or let the UAV take off automatically if the mission includes an automatic takeoff procedure.
9. Monitor the UAV's flight from the ground control station, checking telemetry data such as altitude, speed, and battery levels.
10. If necessary, adjust the mission parameters mid-flight using the ground control station.
11. Once the mission is complete, the UAV will return to the designated home point and land automatically, or you can take manual control for landing.





MISSION PLANNING

Note: Only functional for Mega 2560 Boards with GPS

Waypoint – the drone will travel between those points

Time PosHold – Drone will wait X number of 00 seconds then move to the next waypoint

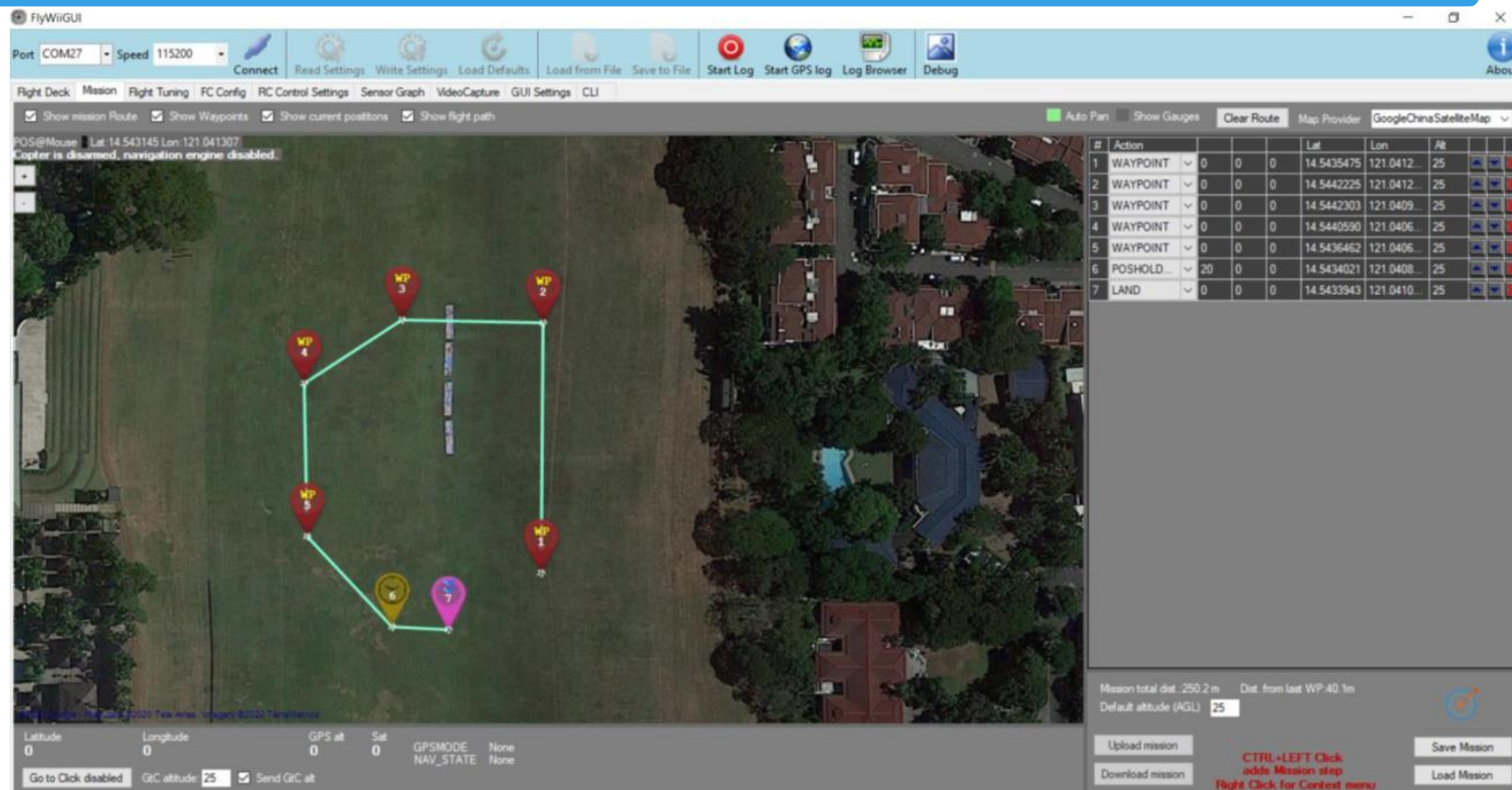
Unlimited PosHold – once the drone reaches this point it will hover and wait till you switch out of Mission mode

Land – the drone will land once it has reached this point (Must be placed at the end of the mission)

RTH – the Drone will fly back to home position (Must be placed at the end of the mission)

0: RTH and hover at Last Waypoint Altitude
1: Land at RTH

Default Alt – Altitude in meters (for first Mission test waypoint with altitude 2m-3m Above Ground Level) And set missions with 2m-3m altitude with Nav speed of 100cm/s.



RC Control Setting Tab – activate Baro , Mag , Mission

To start mission takeoff aircraft in stabilize mode up to 1-2meter altitude then switch the aux switch to mission mode .

Any time you can switch out of it on hold or stabilize mode

MISSION PLANNING

Note: Only functional for Mega 2560 Boards with GPS

Jump – the drone will travel to the selected waypoint and continue the mission from there

WP# - the Waypoint to jump to

REP - how many times to repeat this operations

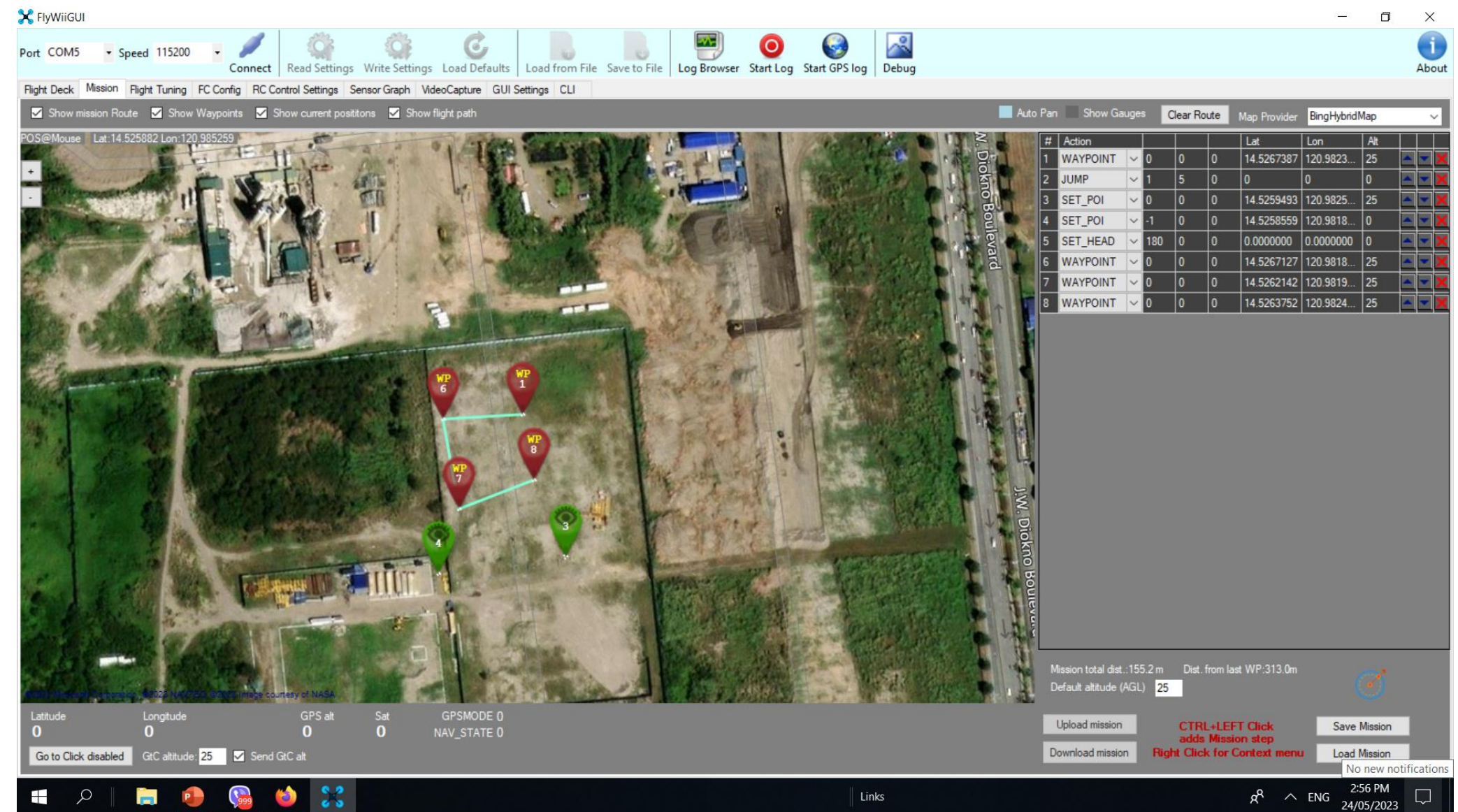
SET_POI – Drone heading would face the Point of interest while flying between waypoint

0 or 1 – Turn POI on

-1 - Turn POI off and resume Nav Heading

SET_HEAD – Drone heading would base the orientation as inputted **1-360**

-1 - Turn Turn Set_head off and resume Nav Heading



RC Control Setting Tab – activate Baro , Mag , Mission

To start mission takeoff aircraft in stabilize mode up to 1-2meter altitude then switch the aux switch to mission mode .

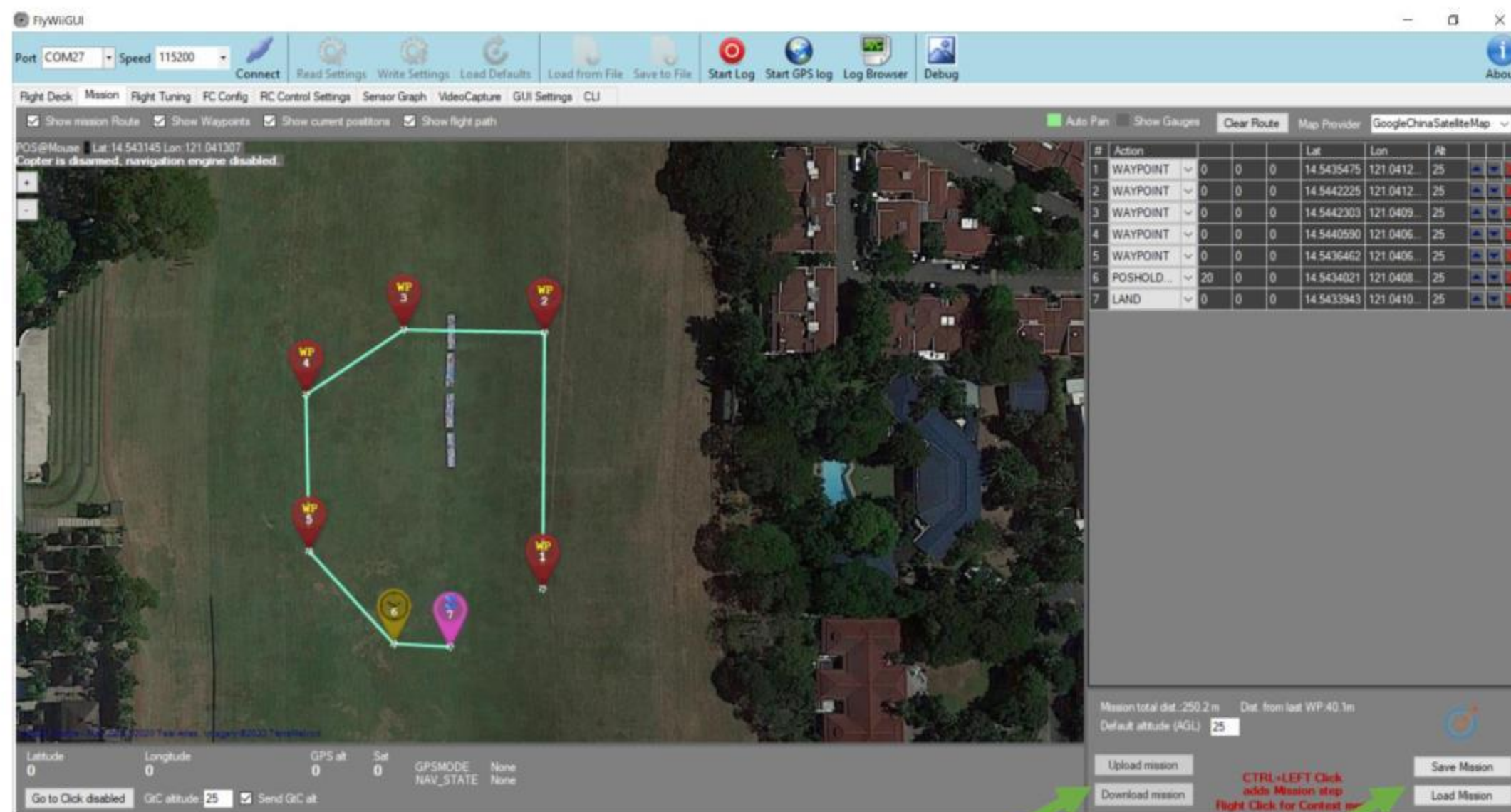
Any time you can switch out of it on hold or stabilize mode



MISSION PLANNING

Prerequisite and process for a good mission , Points to test before performing a mission

1. Drone is flying stable in horizon and Alt hold mode , holding altitude consistently less than 1m variation over 1 minute period . Tune PID and altitude PID when necessary.
2. Drone is flying stable and holding position in GPSHold mode and Alt Mode not deviating with in a 1 x1 Meter Imaginary box , tune PosHold Rate PID when necessary
3. RTH – set RTH Altitude to 0 , Max Nav speed to 100cm/s , set aux switch to RTH ,Baro , Mag and write settings ,Fly the drone 5 Meters away from the Launch site and activate the RTH Aux switch ,see if the drone returns back to home position and holds position when arrive . Tune Navigation Rate PID when necessary

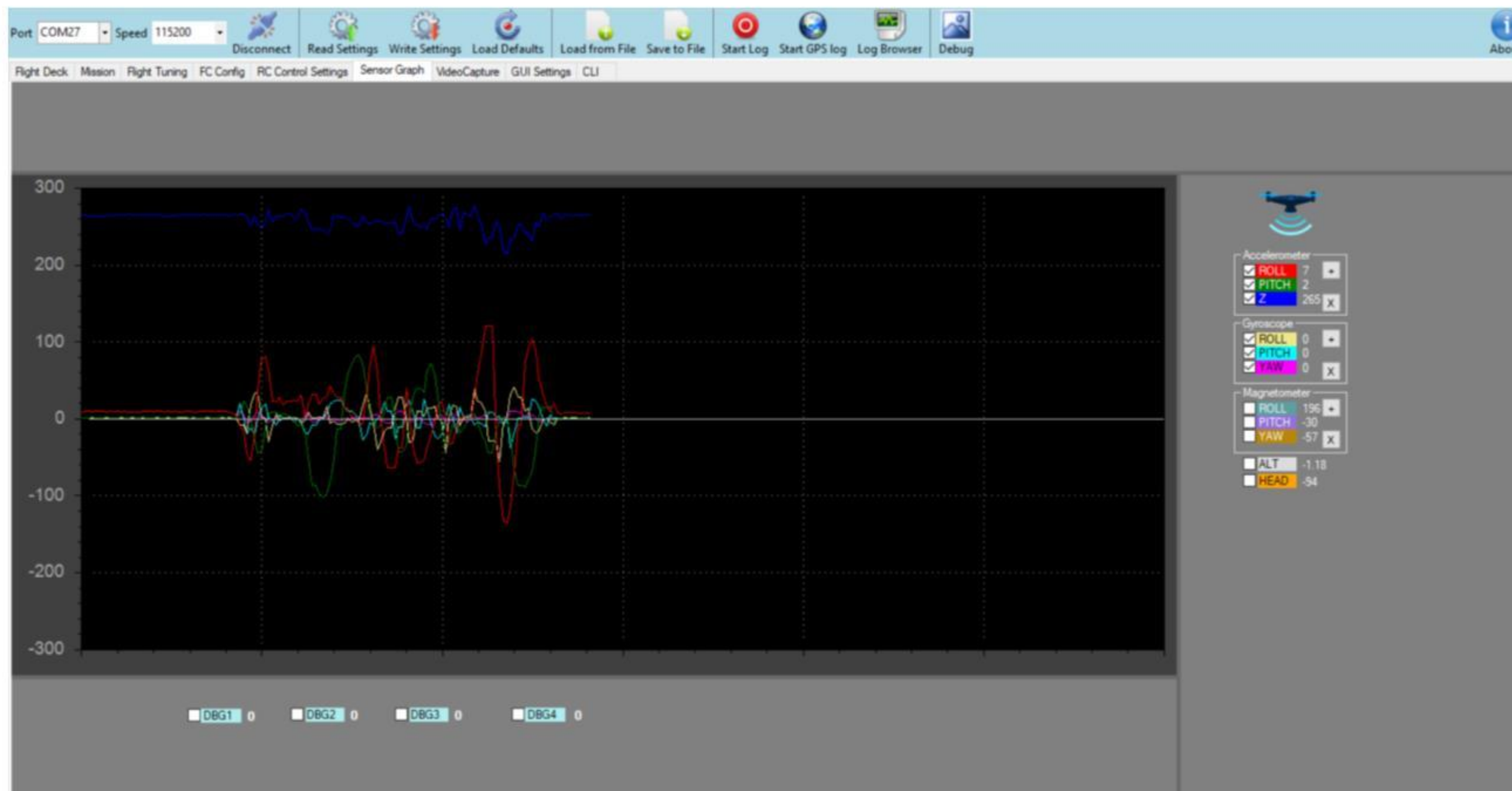


Mission upload to /download from Drone

Mission Save to /Open from File



SENSOR GRAPH



the correct orientation

ACC

Roll Right + no#

Pitch nose down + No#

Z up + No#

GYRO

Roll Right + no#

Pitch nose down + No#

Yaw Right +No#

MAG

Mag & HEAD degrees
corresponds to the compass
0 Degrees is North

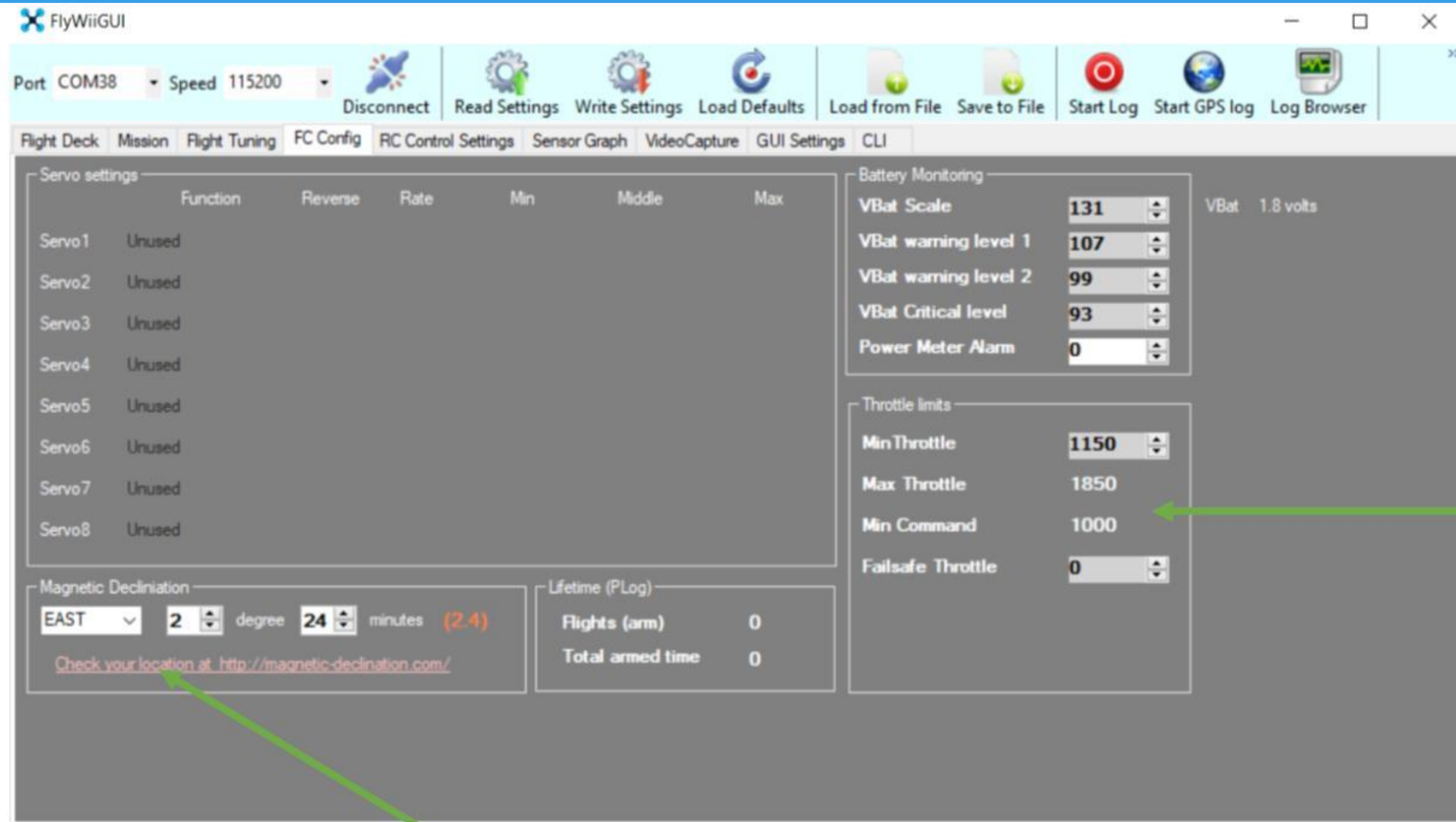
Example : if roll the drone to the right the Accelerometer and Gyroscope graphs would show positive numbers and to the Left Negative numbers

If Lift the drone up Vertically the accelerometer Z axis should shows positive numbers and altitude should show a climb in meters , and if you hold the drone upsidedown Z axis would show Negative numbers

BARO

Alt up +no#

FC CONFIG FUNCTION



MOTOR THROTTLE RANGE PWM TO THE MOTOR
THIS ALSO CONTROLS THE MOTOR IDLE SPEED ON ARM

IMPORTANT TO KNOW THE MAGNETICDECLINATION OF YOUR REGION

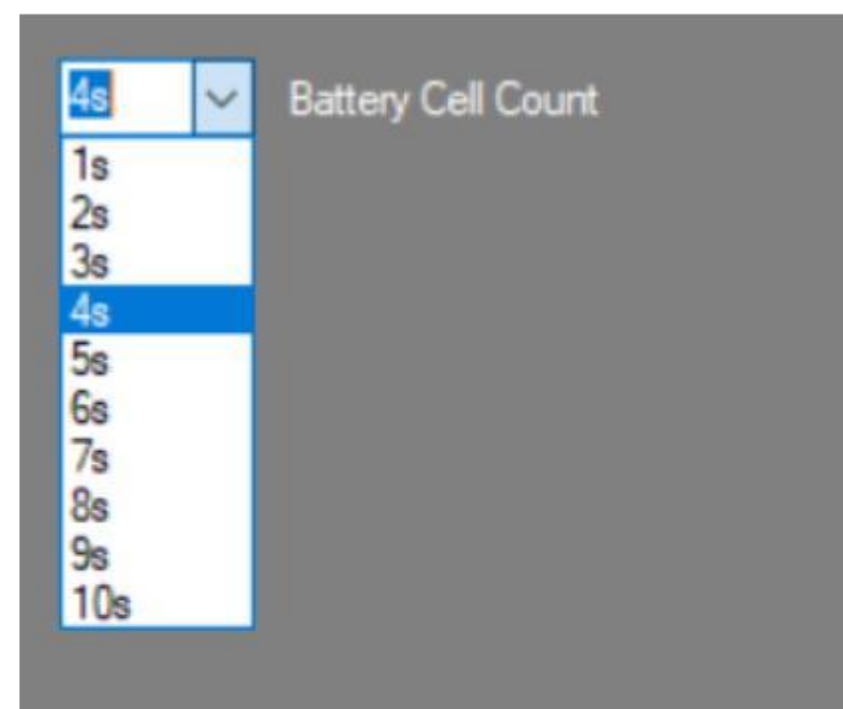
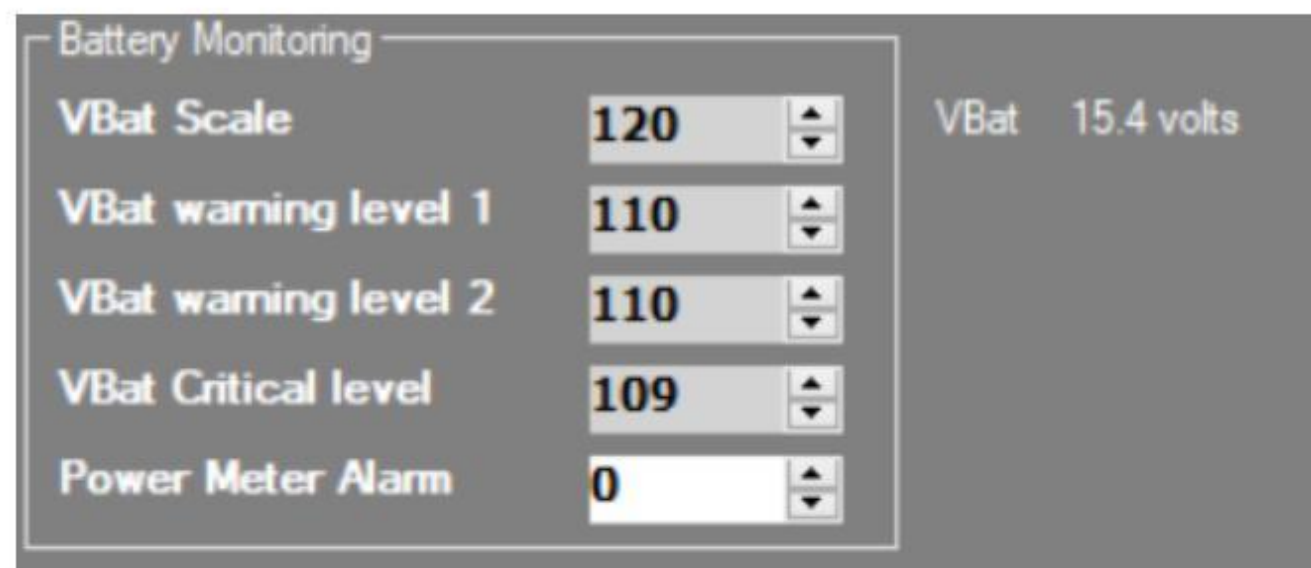
THIS AID ANY AUTONOMOUS FUNCTION THAT REQUIRES COMPASS

- HEADING HOLD
- GPS HOLD
- RTH
- MISSION

CALIBRATE COMPASS AT THE FLIGHT DECK TAB AFTER SETTING THIS UP



BATTERY VOLTAGE CALIBRATION



(FC CONFIG TAB)

BATTERY MONITORING

VBAT SCALE - ADJUST THIS TO MATCH THE BATTERY VOLTAGE OUTPUT USING THE VOLTAGE ALARM INDICATOR

VBAT WARNING LEVEL – IDENTIFY THE NOTICE WHEN THE BATTERY DROPS TO THIS VOLTAGE

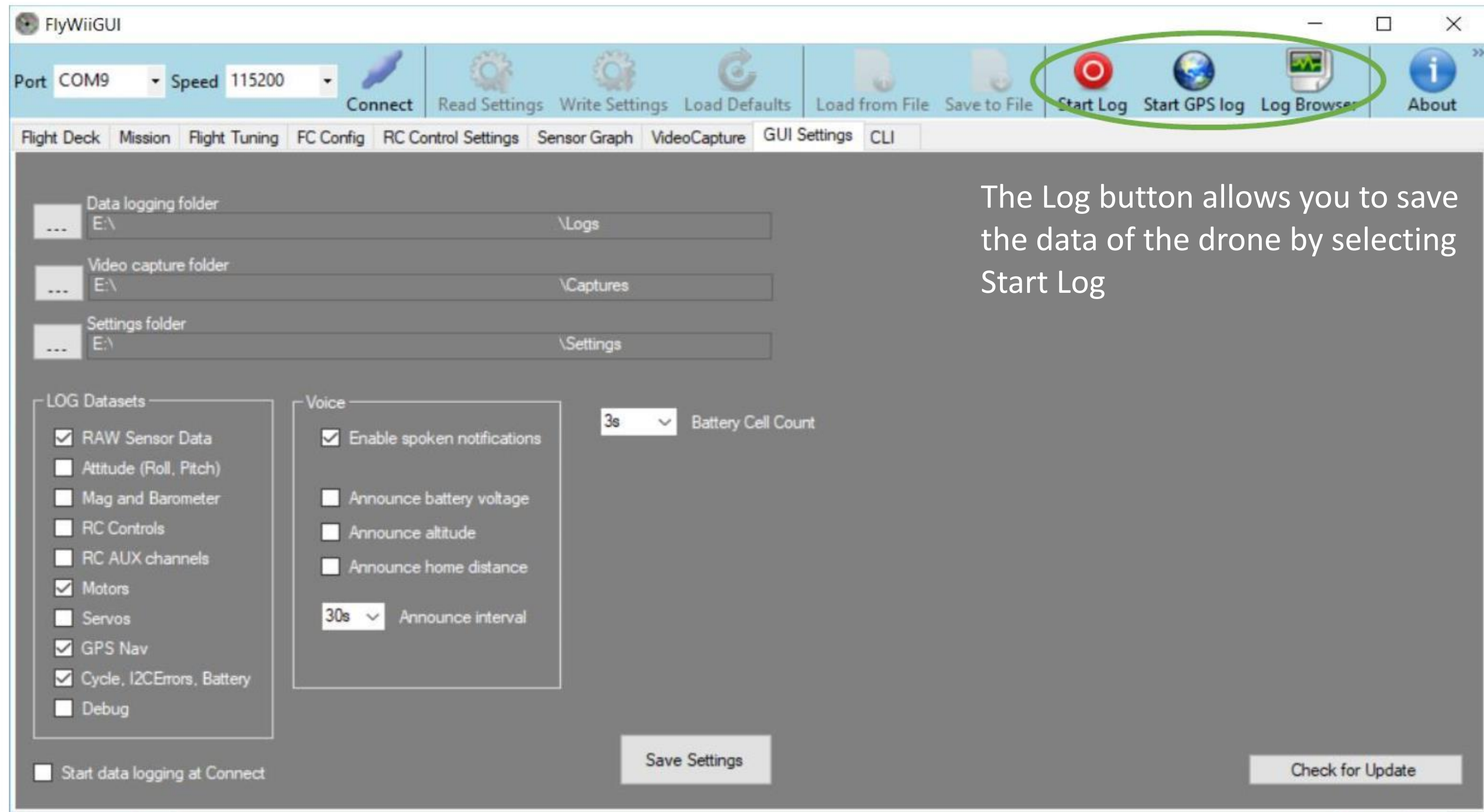
(GUI SETTINGS TAB)

BATTERY CELL COUNT- ADJUST THIS DEPENDING ON THE NUMBER OF CELLS

THIS BOARD SUPPORTS 2S-4S BATTERY

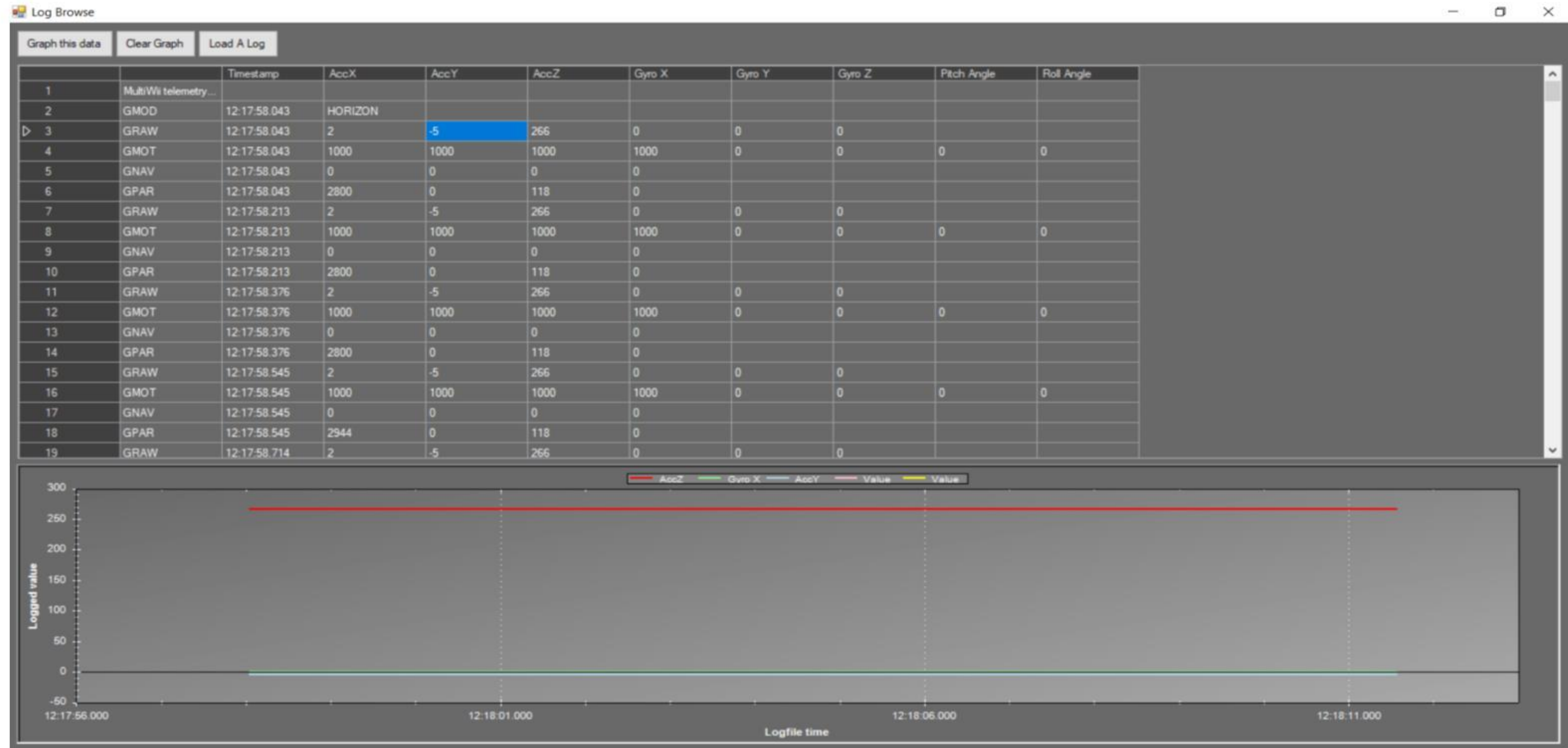


MISSION PLANNING



GUI Settings (where you save your PID ,Flight Logs and Video Logs)

LOG BROWSER



Log Browser this is selected in the Log button on top its use as a visual from data gather from the IMU , RC input and sensor inputs with GPS coordinates this also outputs as CSV for viewing on excel spread sheet

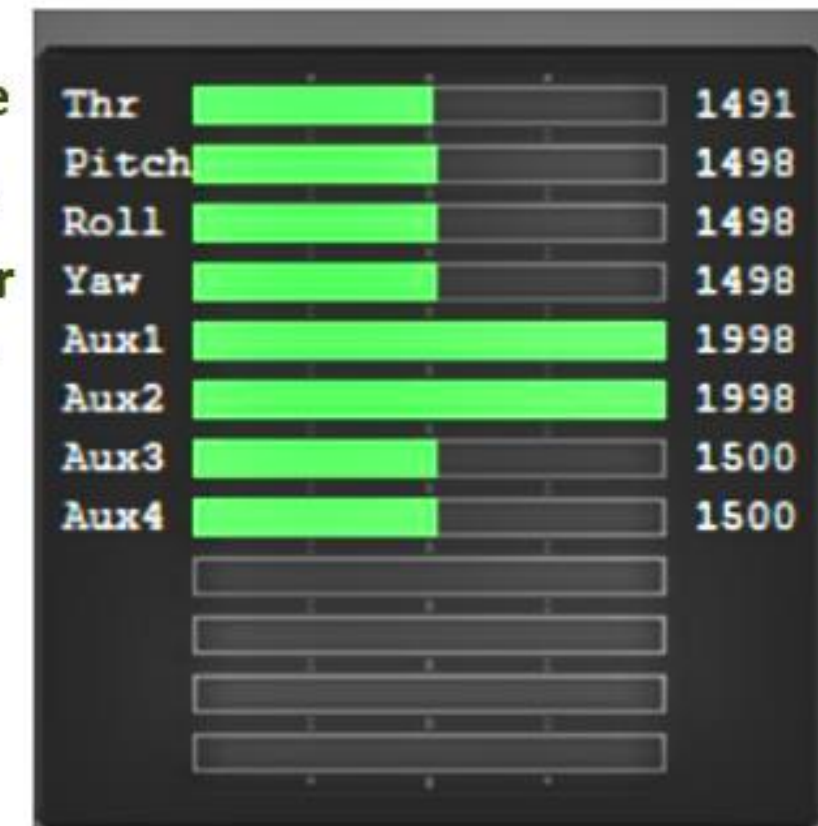
RADIO CONTROL

RC Mapping and Remote

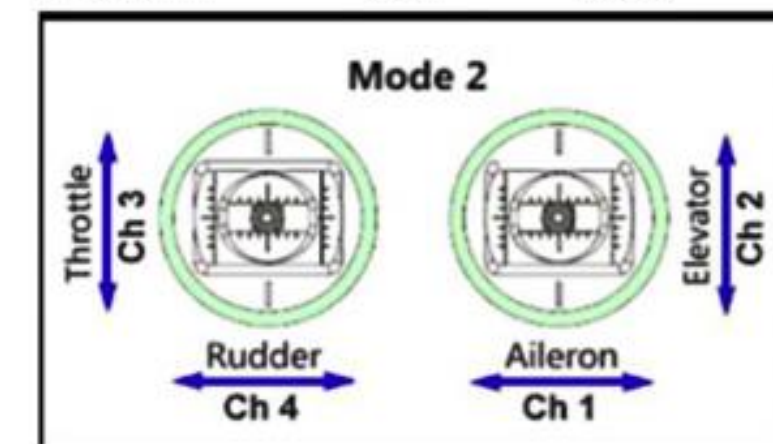


To ensure the correct orientation of your control and PWM pin installation, follow the FlywiiGUI arrangement as follows:

- Throttle
- Aileron
- Elevator
- Rudder
- Aux1
- Aux2
- Aux3
- Aux4



PWM 1000 1500 2000



RADIO CONTROL

RC Display

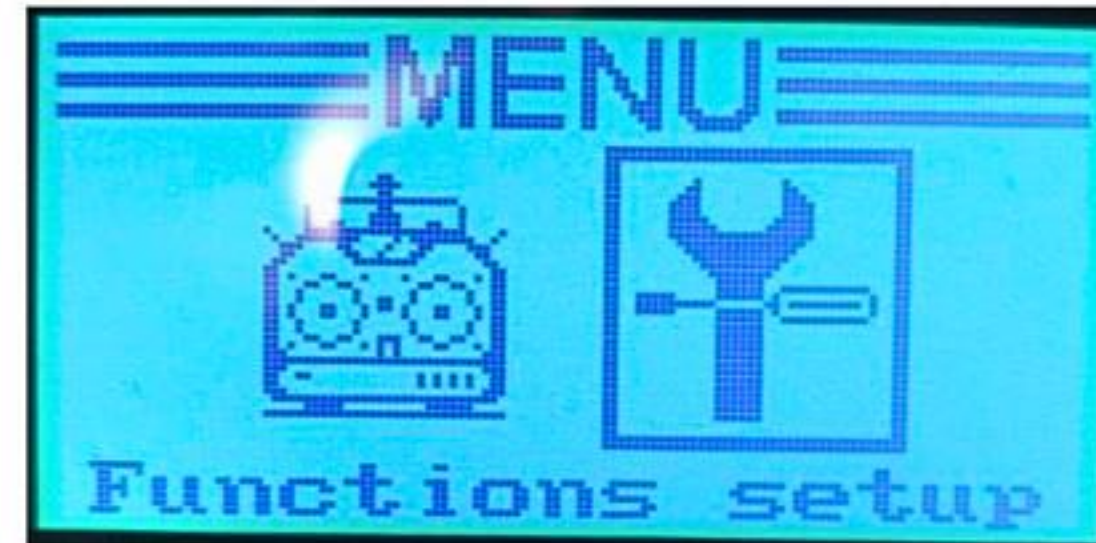
This is used to see if the RC output matches the required input of the Synerduino, as seen in the FlywiiGUI main dashboard's Flight Deck tab.

- Press OK for 1 sec
- Enter Systems
- Choose RX Setup
- Choose Display
- Test the channels by moving the sticks and switches
- Hold the Cancel button for 3 seconds to set and save the profile when exiting

Good news for the i6 Series Radio: this function is aligned with the Synerduino codes.

Note: If you notice that the PWM isn't correct or if the display output doesn't match what the Flywii is doing, you may need to reverse it.

See the manual for other radios, as the channel output may differ.



RADIO CONTROL

Aux Switches



Flight modes allows for additional access functions to your drone's capabilities.

It can be setup using the Aux switches:

ARM
Baro
Altitude
GPS Hold
Mag
GPS Home
Mission
Trigger
Land



PWM 1000 1500 2000

RADIO CONTROL

Fail Safe



Your Drone should enter this modes when it gets disconnected from the remote for whatever reason

it 's a safety function as important as getting it connected in the first place.

Two Option can be configured

- GPS Home (RTH)– this sets the drone into return to home mode right to the Launch location only works when GPS is available
- Land - the simplest way is to quit all other flight modes and throttle down . Commonly use in none GPS Drones

This require setup both on Remote and FlyWiiGUI

RADIO CONTROL

FS or TYG i6 remote example for Fail safe

Press OK for 1 sec

Enter Systems

Choose RX Setup

Choose Failsafe

Choose Channel to set failsafe to

Move the stick or Aux switch to its fail safe position
Eg. GPS Home Mode (Ch5 or Ch6 where ever you set that mode in) or throttle down Stick on Ch3

Hit ok button

Hold Cancel Button for 3sec to set when exiting the failsafe menu

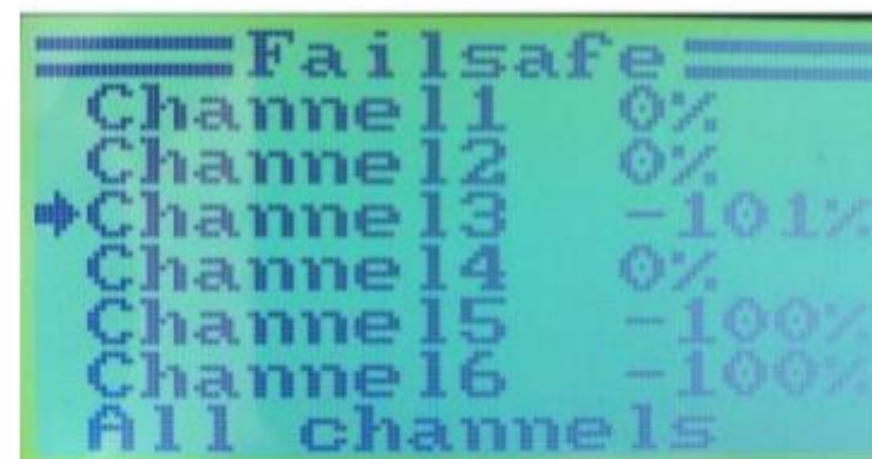
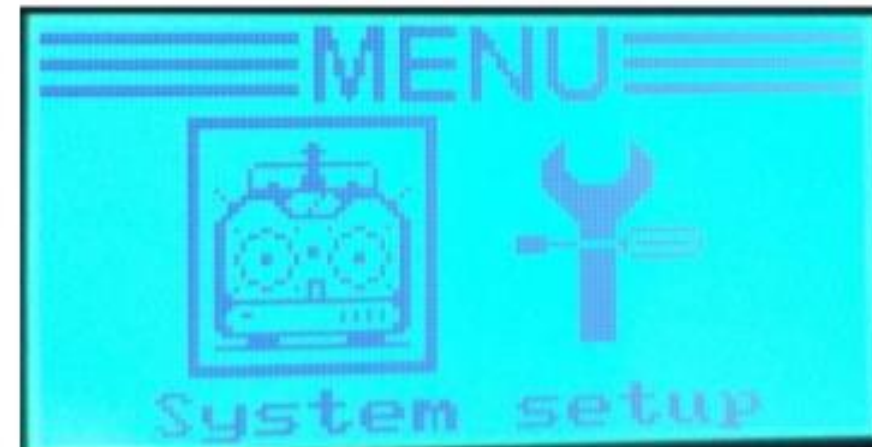
You may enter in again to see if its set properly

Attention:

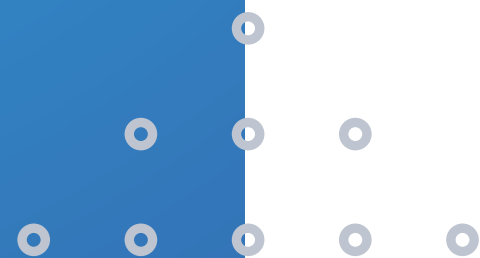
The Receiver will enter this mode when radio link is lost from the Transmitter

Switch transmitter off to test this function

Make sure props are remove before doing so

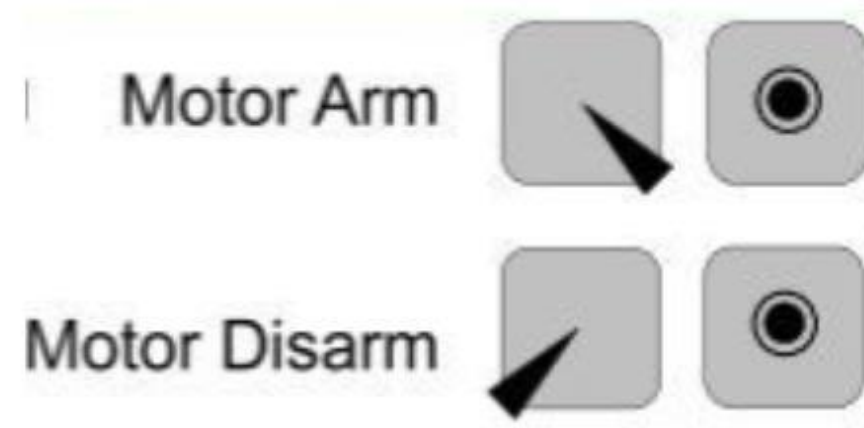


PRE-FLIGHT



And your much Done on your setup

For Mode 2 Hold 2 seconds



Cannot Arm Motors

when on GPS Home , GPS Hold ,
Mission Flight modes & when USB
is plugged in . (pls use Bluetooth
telemetry)

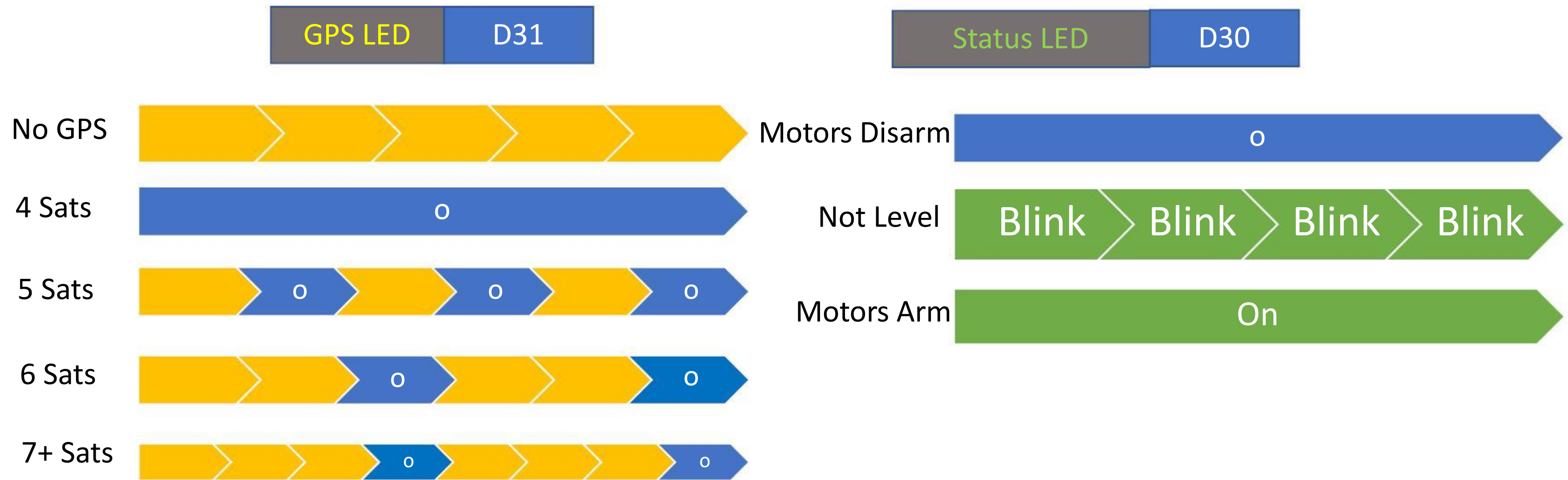
Tests motors with Props off

Baro and Mag preferably switch off
when Arming

Pls calibrate ACC and Mag in the
Dashboard



LED Indicator



indicate a valid GPS fix by flashing the LED

- led work as sat number indicator
- No GPS FIX -> LED blinks constant speed
- Fix and sat no. below 5 -> LED off
- Fix and sat no. ≥ 5 -> LED blinks, one blink for 5 sat, two blinks for 6 sat, three for 7 +



SYNERFLIGHT

SYNERDUINO

ARDU 2560