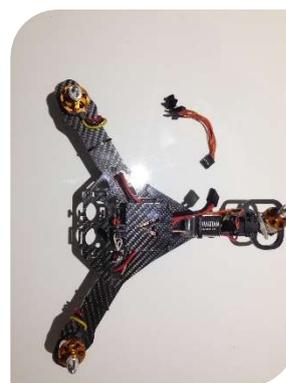


ARMATTAN

Tricopter 258, 355 Setup Guide



ARMATTAN Tricopter를 구매해 주셔서 감사합니다.
- Tricopter 설정에 있어서 주의사항을 **Baseflight** 기준으로 설명합니다.



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1. 프롭과 모터의 회전방향



※ Baseflight와 Cleanflight는 방향을 잘못 설명하고 있습니다. 우리는 상기 그림과 같은 설정을 추천합니다.

COM4 115200 Disconnect Auto-Connect Gyro Accel Mag Baro GPS Sonar

20:10:45 -- Serial port successfully closed
20:10:53 -- Serial port successfully opened with ID: 7
20:10:53 -- Unique device ID received - 0x670ff505552867067152627
20:10:53 -- Running firmware released on: Oct 2 2015

Setup Configuration PID Receiver Mode Selection Servos GPS Motor Testing Sensor Data Logging Backups CLI

Mixer

Features

- Enable PPM input (and disable PWM input)
- Enable Battery voltage monitoring
- Enable in-flight level calibration
- Enable Serial-based receiver
- Don't spin the motors when armed ※ 체크
- Enable servo gimbal
- Enable 3rd serial port
- Enable LED ring support
- Enable GPS (PPM or 3rd serial port required)
- Enable failsafe settings on PPM/PWM signal loss
- Enable sonar
- Enable FrSky-compatible telemetry output
- Enable Battery current monitoring
- Enable VARIO
- Enable 3D mode (for use with reversible ESCs)
- Enable GPS Return to Home for Fixed Wing
- Enable Oneshot (Syncs PWM output with the main loop)
- Enable FastPWM (lowers the PWM pulse length to 1/8th)

Accelerometer & Magnetometer

GPS

Current Sensor

Throttle

Serial Receiver

Battery Voltage

Port utilization: D: 0% U: 0% Packet error: 0 I2C error: 0 Cycle Time: 3505 0.683



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2. PID Tuning

Setup	Configuration	PID Tuning	Receiver	Mode Selection	Servos	GPS	Motor Testing	Raw Sensor Data	Logging	CLI																																																		
		<table border="1"><thead><tr><th>Name</th><th>Proportional</th><th>Integral</th><th>Derivative</th></tr></thead><tbody><tr><td>ROLL</td><td>3.1</td><td>0.029</td><td>22</td></tr><tr><td>PITCH</td><td>3.1</td><td>0.029</td><td>22</td></tr><tr><td>YAW</td><td>6.8</td><td>0.039</td><td>0</td></tr><tr><td>ALT</td><td>5.0</td><td>0.000</td><td>0</td></tr><tr><td>VEL</td><td>12.0</td><td>0.045</td><td>1</td></tr><tr><td>Pos</td><td>0.11</td><td>0.00</td><td></td></tr><tr><td>PosR</td><td>2.0</td><td>0.08</td><td>0.045</td></tr><tr><td>NavR</td><td>1.4</td><td>0.20</td><td>0.080</td></tr><tr><td>LEVEL</td><td>9.0</td><td>0.010</td><td>100</td></tr><tr><td>MAG</td><td>4.0</td><td></td><td></td></tr></tbody></table>	Name	Proportional	Integral	Derivative	ROLL	3.1	0.029	22	PITCH	3.1	0.029	22	YAW	6.8	0.039	0	ALT	5.0	0.000	0	VEL	12.0	0.045	1	Pos	0.11	0.00		PosR	2.0	0.08	0.045	NavR	1.4	0.20	0.080	LEVEL	9.0	0.010	100	MAG	4.0			<table border="1"><thead><tr><th>ROLL & PITCH rate</th><th>YAW rate</th><th>TPA</th></tr></thead><tbody><tr><td>0.15</td><td>0.55</td><td>0.05</td></tr></tbody></table>	ROLL & PITCH rate	YAW rate	TPA	0.15	0.55	0.05							
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<input type="button" value="Refresh"/> <input type="button" value="Save"/>																																																												
Port utilization: D: 0% U: 0% Packet error: 0 I2C error: 0 Cycle Time: 3513 0.63																																																												

3. Yaw Reverse

Setup	Configuration	PID Tuning	Receiver	Mode Selection	Servos	GPS	Motor Testing	Raw Sensor Data	Logging	CLI
Model: Tricopter										
Servo 5										
Min		Max		Middle		Rate (%)				
1020		2000		1500		100				
Direction of movement										
Roll		Pitch		Yaw		Throttle		AUX 1		AUX 2
Reverse		<input type="checkbox"/>		<input checked="" type="checkbox"/> ※ 체크		<input type="checkbox"/>		<input type="checkbox"/>		<input type="checkbox"/>
Enable Live Mode: <input type="checkbox"/>										<input type="button" value="Save"/>
<p>※ 마지막으로 Mode Selection에서 각자의 조종기의 AUX값에 따른 설정을 해주시면 됩니다.</p>										