

piDrones

Version 0.1

Don't Do It!

DIY piDrones cost significantly more than £1k yet support (a little) less than a professional drone costing less than £1k. Just buy yourself a DJI Mavic or Spark and get out flying in days rather than building a piDrone over months / years!

Raspberry Pi's

The functions supplied by each piDrone depends primarily on the number of CPUs' performance and the sensors they carry.

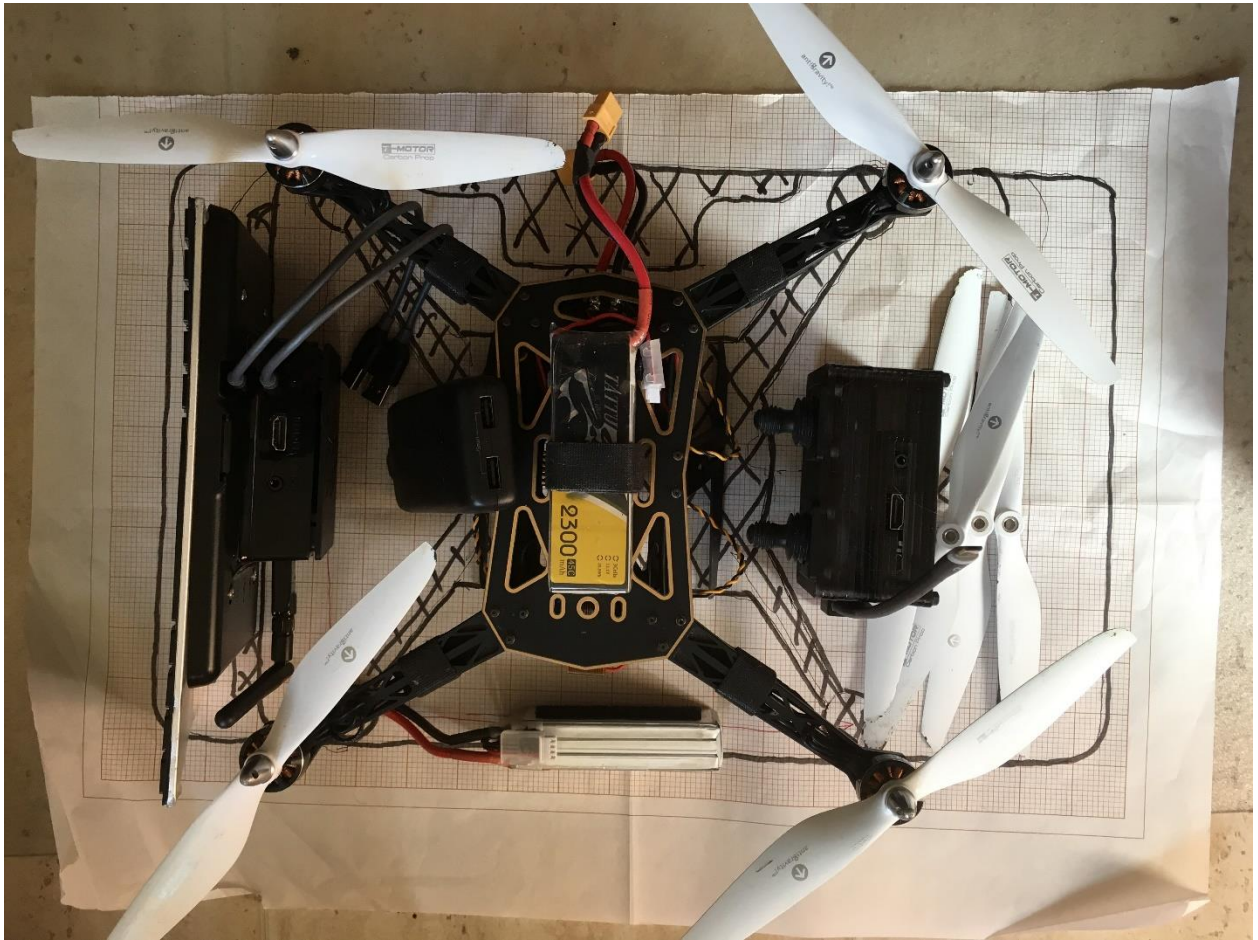
Penelope (Pitstop) is a Raspberry Pi 3B+ 4 1400 MHz CPU Stretch piDrone supporting human-RC-, and autonomous file- and GPS-control flights.



Hermione (Granger) is a Raspberry Pi 3B 4 1200MHz CPUs Jessie piDrone supporting human-RC-, and autonomous file- and GPS-control flights with object avoidance.

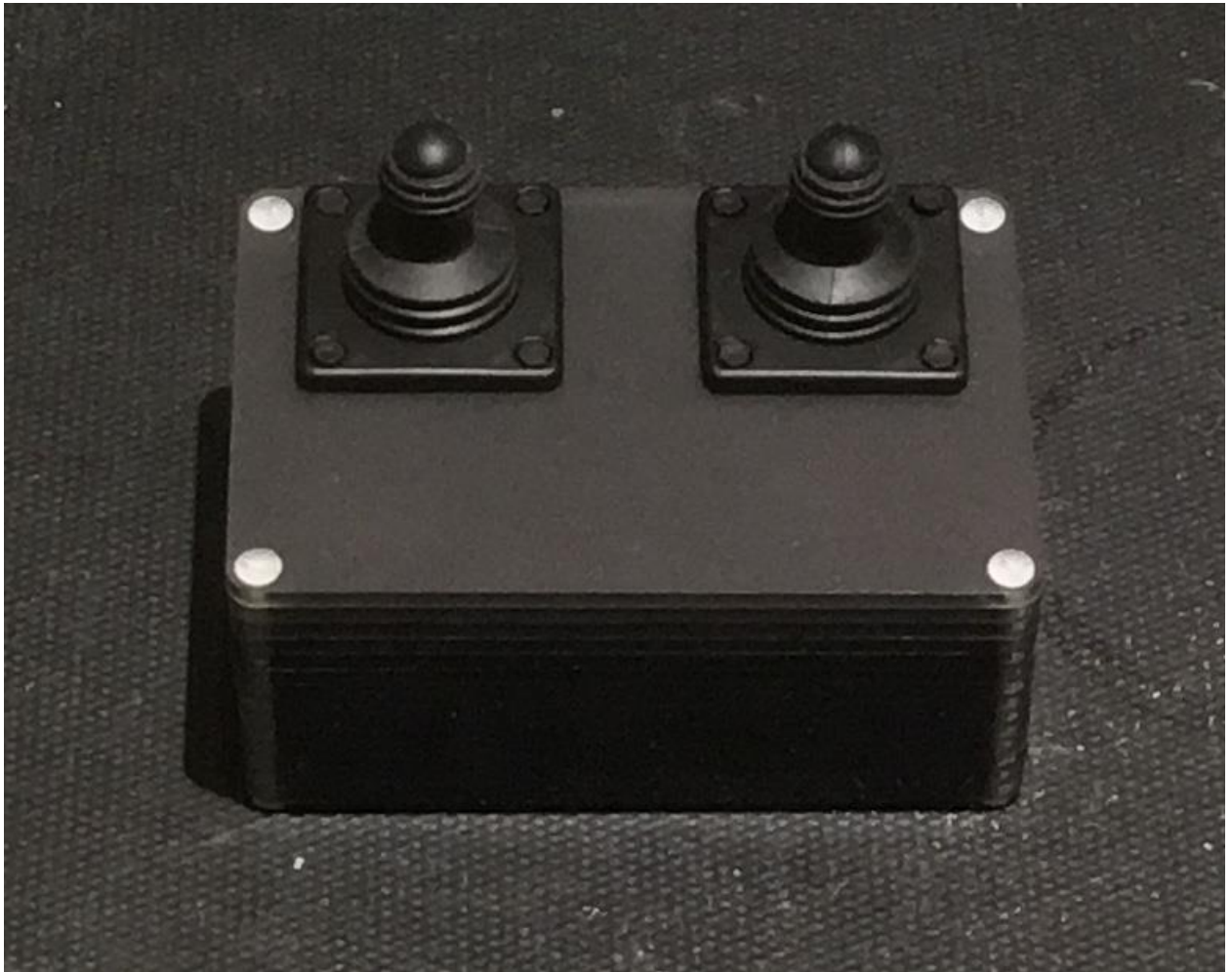


Zoe (Johnny Hall's daughter) is a Raspberry Pi0W single CPU Stretch piDrone supporting human-RC-, and file-control flights.



Master at <https://github.com/PiStuffing/Quadcopter/blob/master/piDrones.pdf>

Ivy is a Raspberry Pi B3+ Stretch piDrone supporting the human RC (remote control). A B3+ is not necessary, it's only used as it was lying around unusade.



A fourth Raspberry Pi is required for remote logging into the piDrones for control.



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Hardware

The hardware frames are no longer available. You'll have to find your own.

Penelope uses eight T-motor CF 13x4.4 props, U3 KV700 motor and Air 40A ESCs, all available from electricwingman.com. Her frame is 75cm diagonally.

Hermione uses eight T-motor wooden 12x4.7 props (unavailable), U3 KV700 motor and Air 40A ESCs available from electricwingman.com. Her frame is 75cm diagonally.

Zoe uses four T-motor four T-motor CF antigravity! 9x3 props (unavailable), Air 2005/2000KV motors (unavailable) and Air 15A ESCs available from electricwingman.com. Here frame is 40cm diagonally.

Sensors

MPU-9250 IMU is required for accelerometer, gyrometer and magnetomer sensors available from pimoroni.com

Garmin LiDAR-Lite v3HP is required for ground-facing vertical distance tracking available from robotshop.com

RPi camera is required for ground-facing lateral distance tracking available from pimoroni.com

u-blox NEO-M8T GPS is required for GPS tracking available from drotek.com.

Grayhill-67a is required for RC joysticks available from avnet.com.

Math(s)

I found this article useful reminding me of math(s) lost long ago from my brain:
<https://scholarsarchive.byu.edu/cgi/viewcontent.cgi?article=2324&context=facpub>

Installation

Basic Configuration

- Use [Etcher](#) to write the SD card with the latest [Raspbian Lite](#) image
- In windows in the root directory of the SD card, create an SSH file to enable it

```
echo hello > ssh
```

- Boot up your RPi with SD card, keyboard, mouse, monitor and WAP / soft AP supporting WiFi dongle installed (no WiFi dongle needed for 3B and Zero-W)

Master at <https://github.com/PiStuffing/Quadcopter/blob/master/piDrones.pdf>

- raspi-config to set hostname, GPU memory (128MB), enable I2C, overclock to 1GHz, disable overscan, disable serial UART, enable camera support and SSH server. Do this incrementally to make sure each change takes effect in /boot/config.txt
- `sudo apt-get update`
- `sudo apt-get dist-upgrade`
- `sudo apt-get install i2c-tools python-smbus python-dev python-setuptools python-picamera python-gps python-serial git ftp udhcpd hostapd`
- edit /boot/config.txt adding

```
dtparam=i2c_arm_baudrate=400000
```

- while in /boot/config.txt, disable pointless functions thus

```
dtparam=audio=off
start_x=0
```

- If you are using a Pi3 or Zero-W, you may want to disable Bluetooth in /etc/modprobe.d/raspi-blacklist.conf thus:

```
# Wi-Fi
# blacklist brcmfmac
# blacklist brcmutil

# Bluetooth
blacklist btbcm
blacklist hci_uart
```

Likewise if you're using an WiFi USB dongle, you can disable the internal one by removing the '#'s for that pair of lines.

- If you are using a B2 V1.2, it can be overclocked to 1.2GHz thus in /boot/config.txt

```
arm_freq=1200
core_freq=500
sdram_freq=600
force_turbo=1
over_voltage=6
```

- If you are using multiple USB UART devices (i.e. GPS and Scansweep in Hermione's case), it's worth linking the USB tty to a unique name for each. In /etc/udev/rules.d add a file such as '99-usb-serial.rules containing something like this:

```
SUBSYSTEM=="tty", ATTRS{idVendor}=="0403", ATTRS{idProduct}=="6015",
ATTRS{serial}=="DO004VY5", SYMLINK+="ttySWEEP"
SUBSYSTEM=="tty", ATTRS{idVendor}=="067b", ATTRS{idProduct}=="2303",
SYMLINK+="ttyGPS"
```

The details of what to fill in come from /var/log/messages as a USB UART is plugged in. Also /etc/default/gpsd and Quadcopter.py to reference these tty* names instead of ttyUSB*. More details here: <http://hintshop.ludvig.co.nz/show/persistent-names-usb-serial-devices/>

- Add hardware PWM

```
git clone -b v2 https://github.com/metachris/RPIO
cd RPIO
```

check mailbox.c code present in source/c_pwm/mailbox.c

```
sudo python ./setup.py install
cd ~
```

- Add I2C variant for joystick

```
git clone https://github.com/kplindegaard/smbus2
cd smbus2
sudo python ./setup.py install
cd ~
```

- Add Quadcopter code

```
git clone https://github.com/PiStuffing/Quadcopter
cp Quadcopter/qc.py .
cp Quadcopter/fp.csv .
cp Quadcopter/Quadcopter.py .
cd ~
```

Wireless Access Point Network Configuration

This is based on <https://www.raspberrypi.org/documentation/configuration/wireless/access-point.md>.

Install required software elements

- `sudo apt-get install dnsmasq hostapd`
- `sudo systemctl stop hostapd`
- `sudo systemctl stop dnsmasq`

Set up the static IP address

- `sudo vi /etc/dhcpd.conf`


```
interface wlan0
    static ip_address=192.168.42.1/24
```
- `sudo service dhcpd restart`
- `sudo mv /etc/dnsmasq.conf /etc/dnsmasq.conf.org`
- `sudo vi /etc/dnsmasq.conf`


```
interface=wlan0
usually wlan0
dhcp-range=192.168.42.2,192.168.42.20,255.255.255.0,24h
```

Set up the access point

- `sudo vi /etc/hostapd/hostapd.conf`


```
interface=wlan0
```

Master at <https://github.com/PiStuffing/Quadcopter/blob/master/piDrones.pdf>


```
driver=nl80211
ssid=HoGWAP
channel=1
wmm_enabled=0
wpa=1
wpa_passphrase=HoG3.141592654
wpa_key_mgmt=WPA-PSK
wpa_pairwise=TKIP
rsn_pairwise=CCMP
auth_algs=1
macaddr_acl=0
```

Enable hostapd

- `sudo vi /etc/default/hostapd`

```
DAEMON_CONF="/etc/hostapd/hostapd.conf"
```

Comment out any "NETWORK={" in /etc/wpa_supplicant/wpa_supplicant.conf

Edit /etc/hostname to ensure the domain name is included - in my case, the domain is called local, and the hostname is pidrone, so /etc/hosts reads

- `pidrone.local`

Next assign static IP address for the piDrone, where pidrone is zoe, hermione or penelope.

- `sudo vi /etc/hosts`

```
127.0.1.1 pidrone.local
192.168.42.1 pidrone.local pidrone
```

Check, double check, and triple check that you've done all the above steps, and then finally

- `sudo reboot`

To backout temporarily to allow for O/S updates etc

- `sudo vi /etc/default/hostapd`

```
DAEMON_CONF=""
```

- Reinstate any "NETWORK={" enties in /etc/wpa_supplicant/wpa_supplicant.conf
- Comment out the AP interface IP details in /etc/dhcpd.conf
- reboot

Flight Commands

Initial Setup

--tc 1 -h 1150 turns each blade one by one so you can check all are working, and are rotate the connect direction. My code assumes the front top left

-d diagnostics logged to qcstats.csv which when fed into a spreadsheet (e.g. Excel) can show graphs about all key parameters from sensors and resultant actions.

--cc checks or calibrates magnetometer i.e. a 3D compass

Autonomous File Flight Control

-f flightplanfile

The flightplanfile is based on a series of lines like this while flies on a horizontal square. Takeoff and landing are automatic:

```
# - evx is fore / aft velocity in m/s; fore is positive
# - evy is port / starboard velocity in m/s; port is positive
# - evz is up / down velocity in m/s; up is positive
# - time is how long to maintain that speed in seconds
# - name is an arbitrary name put out to console to show flight progress

# evx, evy, evz, time, name

0.0, 0.0, 0.0, 1.0, HOVER
0.25, 0.0, 0.0, 4.0, FORE
0.0, 0.0, 0.0, 1.0, HOVER
0.0, 0.25, 0.0, 4.0, PORT
0.0, 0.0, 0.0, 1.0, HOVER
-0.25, 0.0, 0.0, 4.0, AFT
0.0, 0.0, 0.0, 1.0, HOVER
0.0, -0.25, 0.0, 4.0, STARBOARD
0.0, 0.0, 0.0, 1.
```

Autonomous GPS Flight Control

--cwp – clear previous set of GPS waypoints

--awp – add another GPS waypoint to the list

--gps – fly from the take-off locations to the series of waypoints in turn

Manual File Flight Control

-f flightplanfile

The flightplanfile is based on a series of lines like this while flies on a horizontal square. Takeoff and landing are automatic:

```
# - evx is fore / aft velocity in m/s; fore is positive
# - evy is port / starboard velocity in m/s; port is positive
# - evz is up / down velocity in m/s; up is positive
# - time is how long to maintain that speed in seconds
```

```
# - name is an arbitrary name put out to console to show flight progress
# evx, evy, evz, time, name

0.0, 0.0, 0.0, 1.0, HOVER
0.25, 0.0, 0.0, 4.0, FORE
0.0, 0.0, 0.0, 1.0, HOVER
0.0, 0.25, 0.0, 4.0, PORT
0.0, 0.0, 0.0, 1.0, HOVER
-0.25, 0.0, 0.0, 4.0, AFT
0.0, 0.0, 0.0, 1.0, HOVER
0.0, -0.25, 0.0, 4.0, STARBOARD
0.0, 0.0, 0.0, 1.0, HOVER
```

Manual RC Flight Control

--rc

The piDrone is booted up first to establish the WAP. Then the RC and control RPi are booted, and connected to the piDrone WiFi. From in the control RPi, via a pair of terminal windows, rlogin to both the piDrone and the RC. Start the piDrone (./pidrone) and the RC (python ./RC.py). When you type in “—rr” on the piDrone command line, the RC and piDrone connect, and an auto-takeoff takes place. Thereafter, the RC is under your control. To trigger an auto-landing, push the joysticks inwards towards each other until the landing is initiated; the landing height is also automated.