

How To Fly PhenixPro Devkit

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1.Download Source Code

Download code from github:

```
git clone https://github.com/RobSenseTech/PhenixPro_Devkit
```

compile code under the guidance of [prj_path]/README.md

Note: From now on, we have two branch on github:

- master
- develop

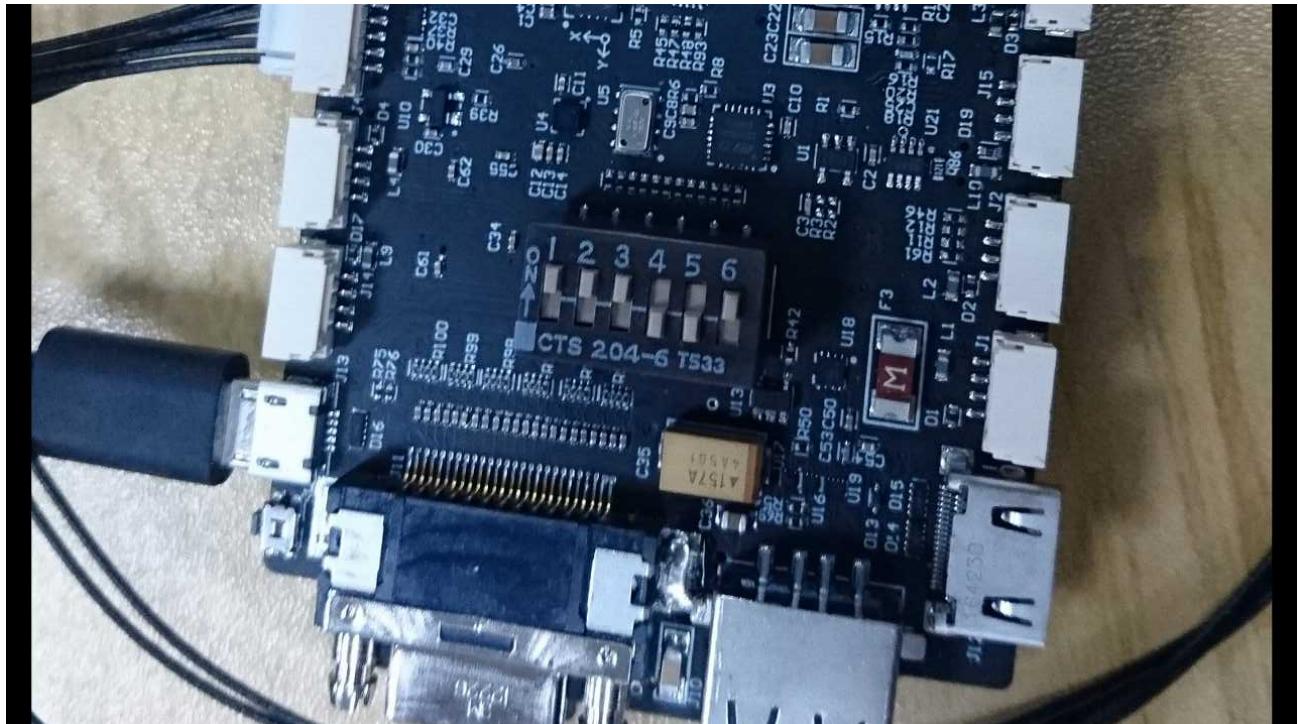
master is the release branch, we only modify code on develop branch, and merge it to master after new code have been tested well.

2.Boot

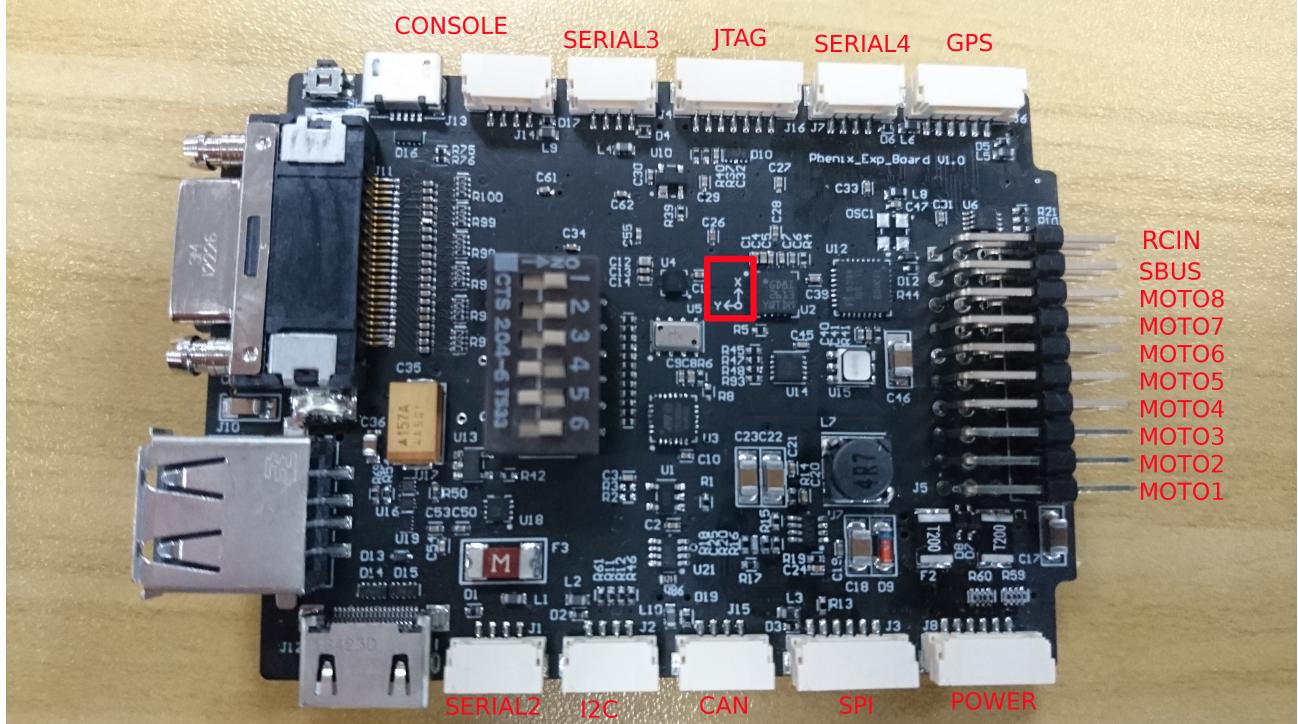
Devkit support boot from sd card, copy these file to sd card:

1. [prj_path]/BOOT.BIN
2. [prj_path]/amp_system/linux_image/devicetree.dtb
3. [prj_path]/amp_system/linux_image/uImage
4. [prj_path]/amp_system/linux_image/uramdisk.image.gz

set DIP switch like the image below(it means boot from sd card):



3. Connect UAV Component



As red words in image above, we can connect UAV component like this:

- Remote control receiver with sbus connect to **RCIN** (pin order from top to bottom is signal, vcc, GND). The **SBUS** port below **RCIN** is used for output sbus signal(not used yet)
- Four motors connected to **MOTO 1 to 4**, respectively (pin order from top to bottom is signal, vcc, GND)
- Ground station can be connected through **SERIAL 4** port on the board with baudrate 115200, while through other **SERIAL** ports with baudrate 57600.
- Connect power distribution board to **POWER**
- UAV head direction is the same as x axis which is marked in red box