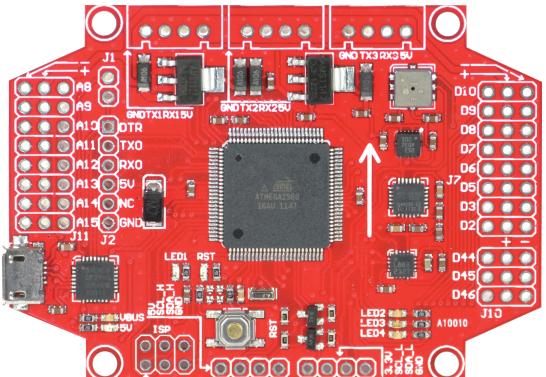
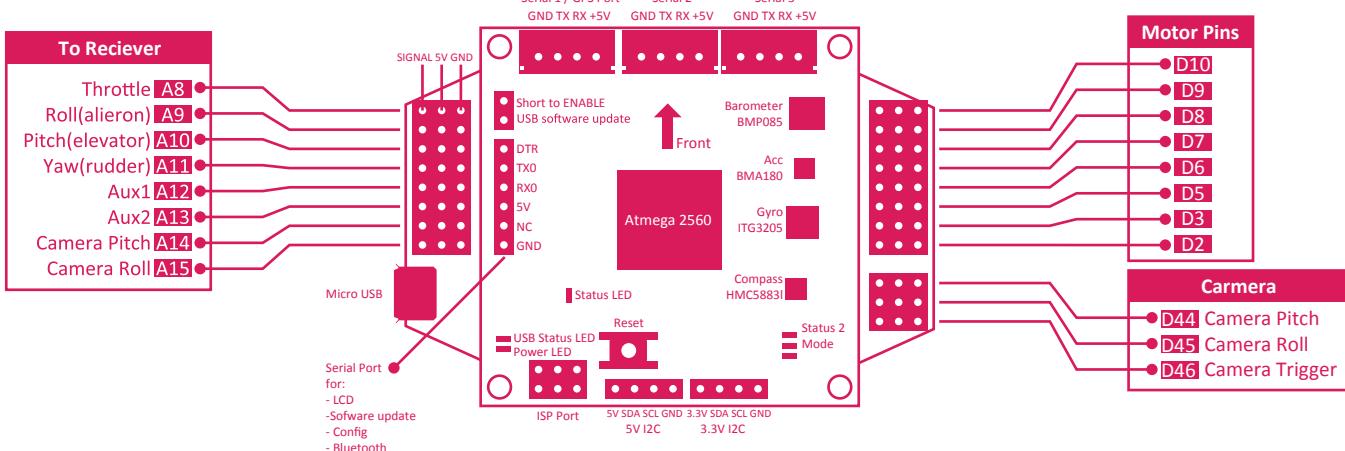


MWC MEGA v1.0



1x Atmega 2560, 256K Flash
9dof + Barometer (ITG 3205 / BMA 180 / HMC5883 / BMP085)
8x Motor output
3x Servo output for Camera
8CH PPM Input (incl. 2x AUX CH)
USB Port on board
3 Stats LED
4x Serial ports, supports GPS Function

Connection Plan



Software Config

Sensors

```
#define FFIMUV2
```

GPS

```
#define GPS
#define GPS_SERIAL Serial1
#define GPS_BAUD 4800 // Your GPS' Baud
```

Camera stabilization system

```
#define SERVO_TILT
```

ESCsCalibration

1. setup all options in config.h to whatever suits your copter
2. activate the define ESC_CALIB_CANNOT_FLY, possibly set high and low values for ESC calibration, if you know what you are doing
3. compile, upload, run --- cannot fly and will use Buzzer/LEDs to indicate finished calibration (after approx 10 seconds)
4. comment the define again, compile, upload
5. test carefully with your ESCs calibrated, fly and have fun

If necessary, the low and high values for the ESCs can be tweaked by changing the values for the defines of ESC_CALIB_LOW and ESC_CALIB_HIGH 2000