Outlook

回复: Re: Testing SKYE2 with PX4

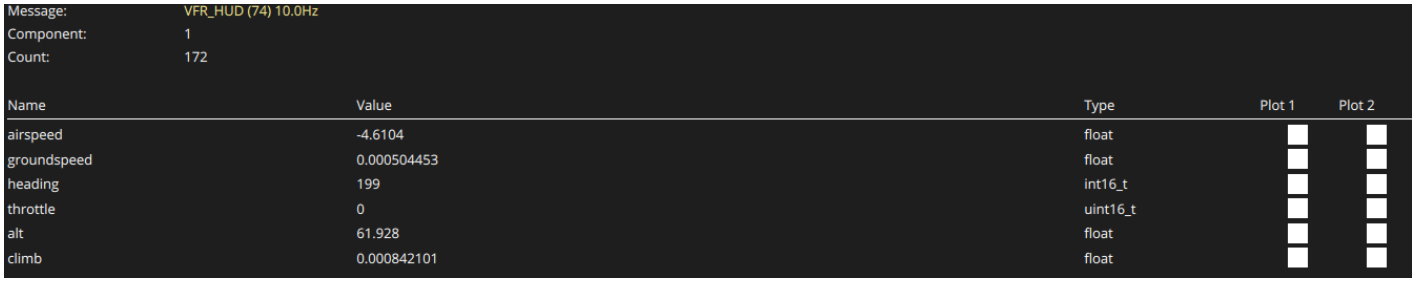
From support@cuav.net <support@cuav.net>
Date Tue 4/29/2025 11:03 AM
To Mohamad Chehadeh <mohamad.chehadeh@droneleaf.io>
Cc lindy <lindy@cuav.net>

Dear sir

That's good. That's right, because the airspeed indicator is usually fixed wing or something, selecting a rotor or other aircraft type ground station will not display the airspeed indicator calibration option, which is an official limitation of PX4.

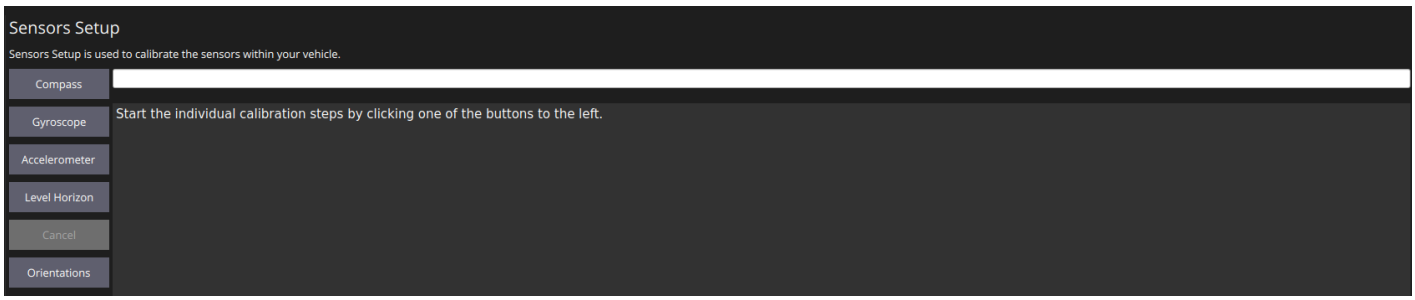
發件人： Mohamad Chehadeh
發送時間： 2025-04-29 14:17
收件人： support@cuav.net
抄送： lindy
主題： Re: Testing SKYE2 with PX4

Hi Iris,
I was using generic hexarotor frame. Then changed to generic fixed wing and the airspeed sensor was detected. I went to PX4 startup script and noticed that `ROMFS/px4fmu_common/init.d/rc.fw_apps` file has additional `
airspeed_selector start` command. I selected the generic hexarotor frame again and ran the command manually `
airspeed_selector start` and got it to work:



Could this note be added to the PX4 guide please?

One more thing, with multirotor airframe the air speed sensor calibration tab does not appear. I guess this is a QGC side issue?

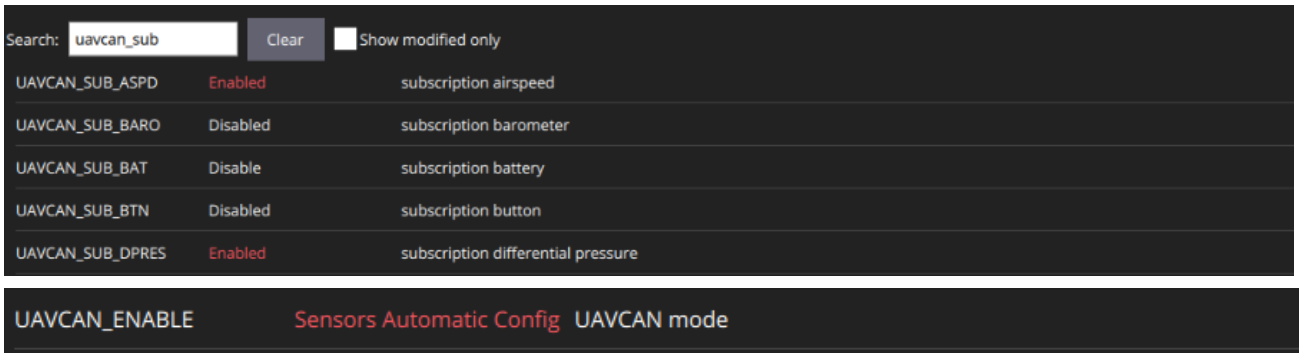


Best Regards,
Mohamad

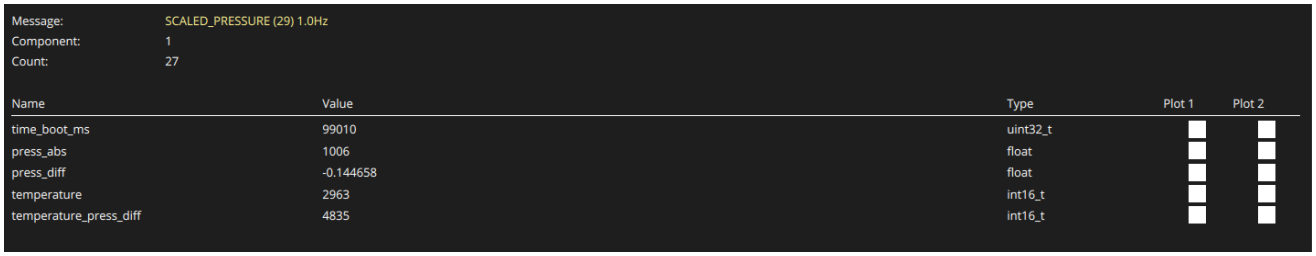
From: Mohamad Chehadeh <mohamad.chehadeh@droneleaf.io>
Sent: Tuesday, April 29, 2025 9:23 AM
To: support@cuav.net <support@cuav.net>
Cc: lindy <lindy@cuav.net>
Subject: Re: Testing SKYE2 with PX4

Hi Iris,
Many thanks for the prompt response.

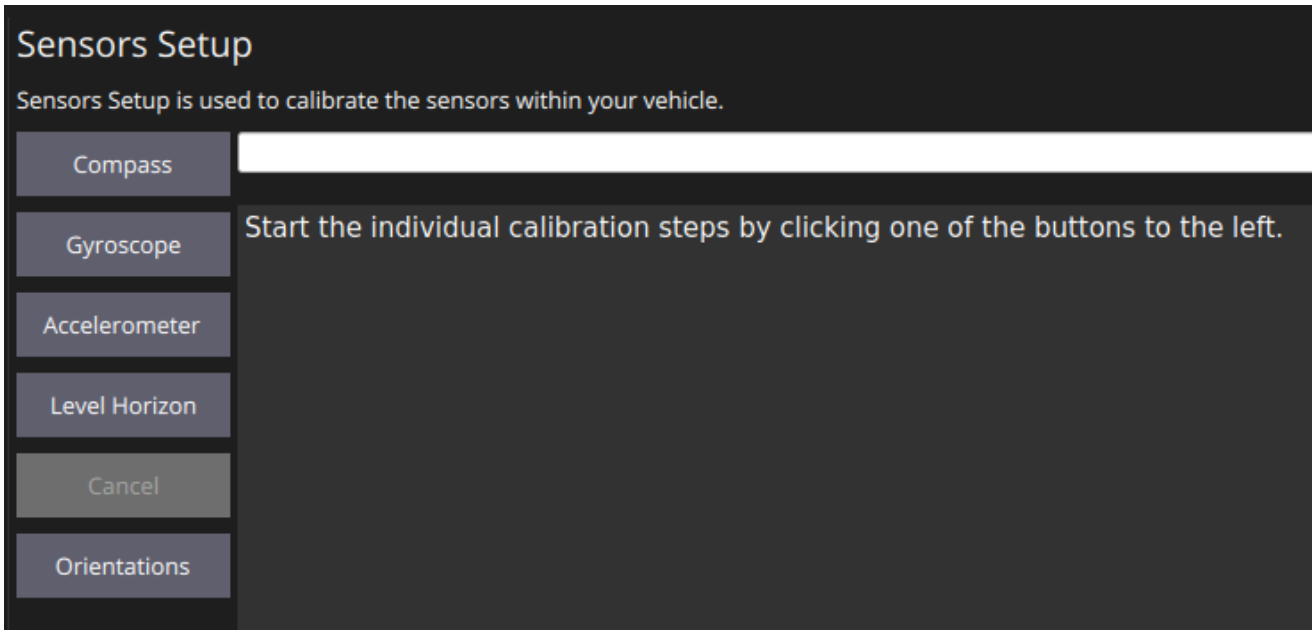
I did the settings as explained. (I am on PX4 1.15.4 stable):

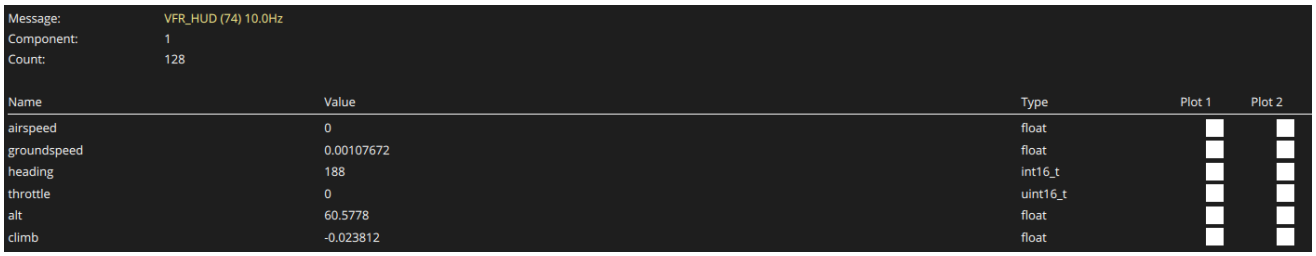


I can get the pressure measurements:



But not airspeed sensor or its measurements:





Message: VFR_HUD (74) 10.0Hz
Component: 1
Count: 128

Name	Value	Type	Plot 1	Plot 2
airspeed	0	float		
groundspeed	0.00107672	float		
heading	188	int16_t		
throttle	0	uint16_t		
alt	60.5778	float		
climb	-0.023812	float		

And I ran `uavcan status` in the mavlink consol (I have connected the sensor to CAN1):

nsh> uavcan status
Pool allocator status:
  Capacity hard/soft: 500/250 blocks
  Reserved: 18 blocks
  Allocated: 10 blocks

UAVCAN node status:
  Internal failures: 0
  Transfer errors: 3869
  RX transfers: 18772
  TX transfers: 5012

CAN1 status:
  HW errors: 39
  IO errors: 39
  RX frames: 57141
  TX frames: 5710
CAN2 status:
  HW errors: 5992
  IO errors: 5992
  RX frames: 0
  TX frames: 5710

ESC outputs:
INFO [mixer_module] Param prefix: UAVCAN_EC
control latency: 0 events, 0us elapsed, 0.00us avg, min 0us max 0us 0.000us rms
Channel Configuration:
Channel 0: func: 0, value: 0, failsafe: 65535, disarmed: 65535, min: 1, max: 8191
Channel 1: func: 0, value: 0, failsafe: 65535, disarmed: 65535, min: 1, max: 8191
Channel 2: func: 0, value: 0, failsafe: 65535, disarmed: 65535, min: 1, max: 8191
Channel 3: func: 0, value: 0, failsafe: 65535, disarmed: 65535, min: 1, max: 8191
Channel 4: func: 0, value: 0, failsafe: 65535, disarmed: 65535, min: 1, max: 8191
Channel 5: func: 0, value: 0, failsafe: 65535, disarmed: 65535, min: 1, max: 8191
Channel 6: func: 0, value: 0, failsafe: 65535, disarmed: 65535, min: 1, max: 8191
Channel 7: func: 0, value: 0, failsafe: 65535, disarmed: 65535, min: 1, max: 8191
Servo outputs:
INFO [mixer_module] Param prefix: UAVCAN_SV
control latency: 0 events, 0us elapsed, 0.00us avg, min 0us max 0us 0.000us rms
Channel Configuration:
Channel 0: func: 0, value: 500, failsafe: 500, disarmed: 500, min: 0, max: 1000
Channel 1: func: 0, value: 500, failsafe: 500, disarmed: 500, min: 0, max: 1000
Channel 2: func: 0, value: 500, failsafe: 500, disarmed: 500, min: 0, max: 1000

Channel 3: func: 0, value: 500, failsafe: 500, disarmed: 500, min: 0, max: 1000
Channel 4: func: 0, value: 500, failsafe: 500, disarmed: 500, min: 0, max: 1000
Channel 5: func: 0, value: 500, failsafe: 500, disarmed: 500, min: 0, max: 1000
Channel 6: func: 0, value: 500, failsafe: 500, disarmed: 500, min: 0, max: 1000
Channel 7: func: 0, value: 500, failsafe: 500, disarmed: 500, min: 0, max: 1000

Sensor 'airspeed':
name: uavcan_airspeed

Sensor 'differential_pressure':
name: uavcan_differential_pressure
channel 0: node id 125 --> instance 0

Sensor 'gnss':
name: uavcan_gnss

Sensor 'gnss_relative':
name: uavcan_gnss_relative

Sensor 'mag':
name: uavcan_mag

Online nodes (Node ID, Health, Mode):
    125 OK   OPERAT

uavcan: cycle time: 168615 events, 4929839us elapsed, 29.24us avg, min 9us max 62482us 167.060us rms
uavcan: cycle interval: 168615 events, 2111.37us avg, min 15us max 62485us 1239.167us rms

Any idea of why would this happen? Could it be a hardware issue? What do you suggest?

Best Regards,
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From: support@cuav.net <support@cuav.net>
Sent: Tuesday, April 29, 2025 7:40 AM
To: Mohamad Chehadeh <mohamad.chehadeh@droneleaf.io>
Cc: lindy <lindy@cuav.net>
Subject: 回复: Testing SKYE2 with PX4

Dear sir

How are you ? Thank you for your feedback.

The SKYE 2 airspeed indicator supports PX4 firmware. You can refer to the information here for parameter configuration and calibration:使用指南(PX4) · SKYE The firmware version is preferably 1.14 or above.

If you have more questions or suggestions about the use of the product, please let me know.
Best Wishes !
CUAV Technical support
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From: Mohamad Chehadeh
Date: 2025-04-29 10:48
To: support@cuav.net
Subject: Testing SKYE2 with PX4

Dear CUAV Support team,
I have a client who have purchased SKYE2 to be used with a PX4 flight controller.

I was able to get differential pressure measurements but not airspeed measurement. There is no user guide in your website for PX4: https://doc.cuav.net/others/skye/en/skye2.html

Does SKYE2 supports PX4? And what firmware version?

Best Regards,
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