


Pestaña configuración (Gestión de parámetros)



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Comando


Configuración

ArduPilot
Armado
Bateria
Motores
Servo OUTPUT
Telemetría
EK2
Compas
GPS
Estadísticas
RC
Waypoint
Misiones


COD	NOMBRE	DESCRIPCION	INTERVALO	VALOR	UNIDADES
SYSID_SW_MREV	Eeprom format version number	This value is incremented when changes are made to the eeprom format.		120.0	
SYSID_SW_TYPE	Software Type	This is used by the ground station to recognise the software type (eg ArduPlane vs ArduCopter). 0 = ArduPlane, 4= AntennaTracker, 10= Copter, 20 = Rover, 40=ArduSub		10.0	
SYSID_THISMAV	MAVLink system ID of this vehicle	Allows setting an individual MAVLink system id for this vehicle to distinguish it from others on the same network		1.0	
SYSID_MYGCS	My ground station number	Allows restricting radio overrides to only come from my ground station. 255 = Mission Planner and DroidPlanner, 252 = AP Planner 2		255.0	
PILOT_THR_FILT	Throttle filter cutoff	Throttle filter cutoff (Hz) - active whenever altitude control is inactive - 0 to disable		0.0	hertz
PILOT_TKOFF_ALT	Pilot takeoff altitude	Altitude that altitude control modes will climb to when a takeoff is triggered with the throttle stick.		0.0	centimeters
PILOT_TKOFF_DZ	Pilot takeoff altitude	Altitude that altitude control modes will climb to when a takeoff is triggered with the throttle stick.		100.0	centimeters
PILOT_TKOFF_DZ	Takeoff trigger deadzone	Offset from mid stick at which takeoff is triggered		100.0	
TELEM_DELAY	Throttle stick behavior	Bitmask containing various throttle stick options. Add up the values for options that you want.		0.0	seconds
		The minimum relative altitude the model will move to			

Restaurar
Guardar


Pestaña conexión (Información y gestión de conexión al vehículo)




Inicio



Conexión



Comando



Configuración

Conectar

Dirección IP:

Puerto:

Desconectar

Registro de conexión


```
INFO: 2018-09-12 12:05:20.801 : [COMANDO ENVIADO ] : Cambiar Modo
INFO: 2018-09-12 12:05:22.921 : [COMANDO ENVIADO ] : Cambiar Modo
INFO: 2018-09-12 12:05:24.832 : [COMANDO ENVIADO ] : Cambiar Modo
INFO: 2018-09-12 12:05:26.872 : [COMANDO ENVIADO ] : Cambiar Modo
INFO: 2018-09-12 12:05:28.984 : [COMANDO ENVIADO ] : Cambiar Modo
INFO: 2018-09-12 12:05:31.105 : [COMANDO ENVIADO ] : Cambiar Modo
INFO: 2018-09-12 12:05:33.673 : [COMANDO ENVIADO ] : Cambiar Modo
INFO: 2018-09-12 12:05:36.928 : [COMANDO ENVIADO ] : Cambiar Modo
INFO: 2018-09-12 23:16:48.167 : OpenGL_accelerate module loaded
INFO: 2018-09-12 23:16:48.479 : Using accelerated ArrayDatatype
INFO: 2018-09-13 00:18:54.486 : OpenGL_accelerate module loaded
INFO: 2018-09-13 00:18:54.721 : Using accelerated ArrayDatatype
INFO: 2018-09-14 17:45:30.690 : OpenGL_accelerate module loaded
INFO: 2018-09-14 17:45:31.006 : Using accelerated ArrayDatatype
INFO: 2018-09-14 17:45:53.971 : >>> APM:Copter V3.6-dev (e0d383c9)
INFO: 2018-09-14 17:45:53.971 : >>> Frame: UNKNOWN
INFO: 2018-09-14 17:45:55.000 : B... : 100.00.110.14550
```

Borrar

Información obtenida

Vehículo

Tipo de vehículo




Firmware


APM:Copter-3.6.0-dev0

Sensores


GPS



Batería




Señal




Sistema

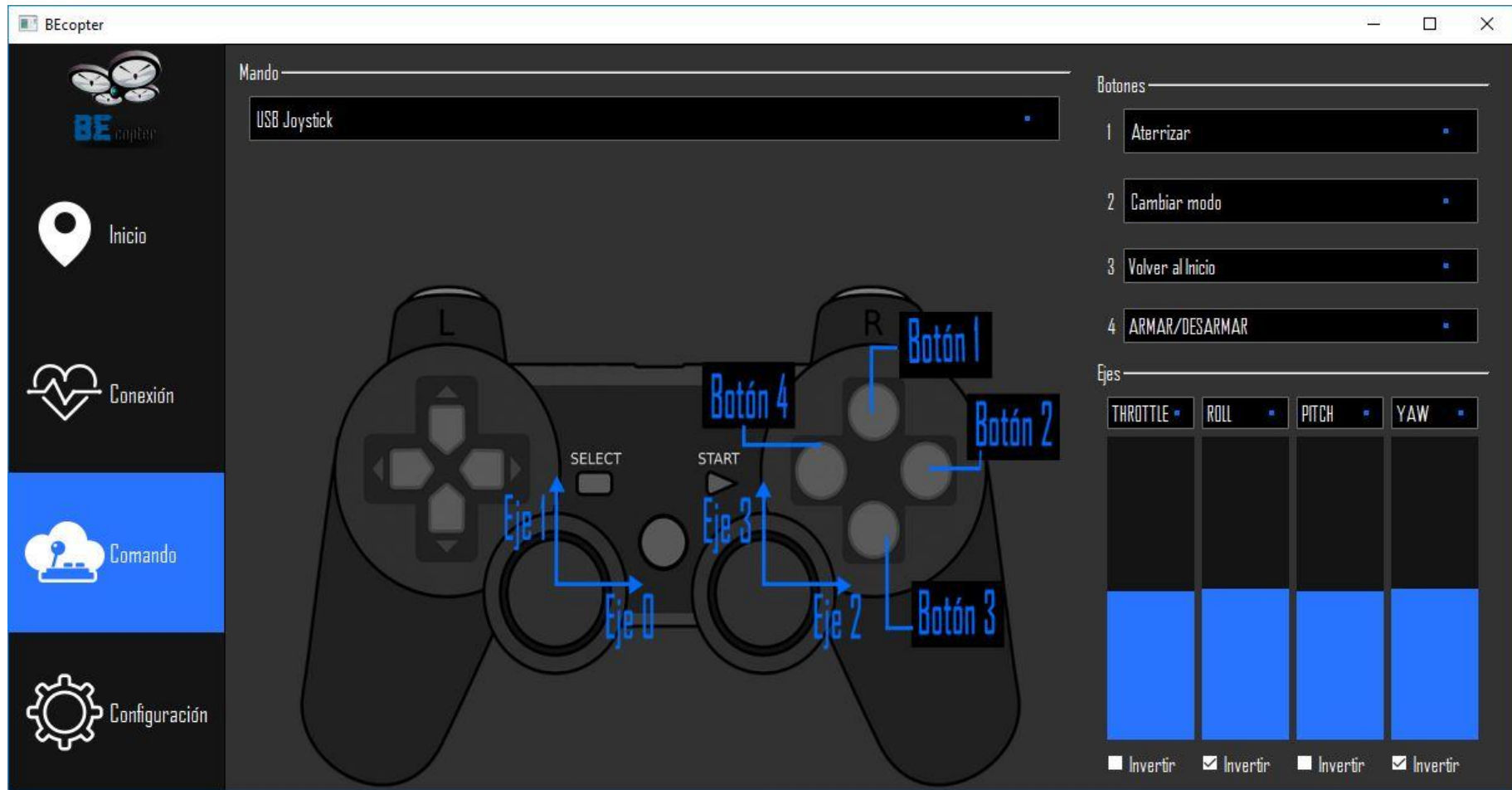
Estado del Sistema



En condiciones para volar



Pestaña comando (Selección y mapeo de funcionalidades)



Pestaña inicial (Visualización de datos y gestión de misiones)

