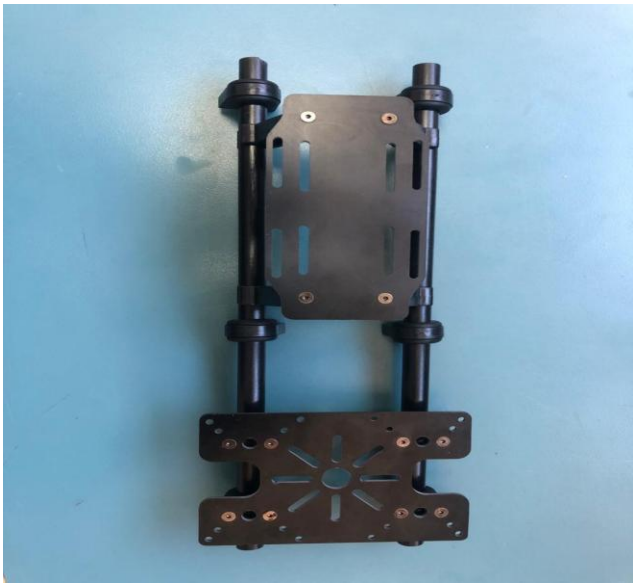
Step 1: Assemble the Holders

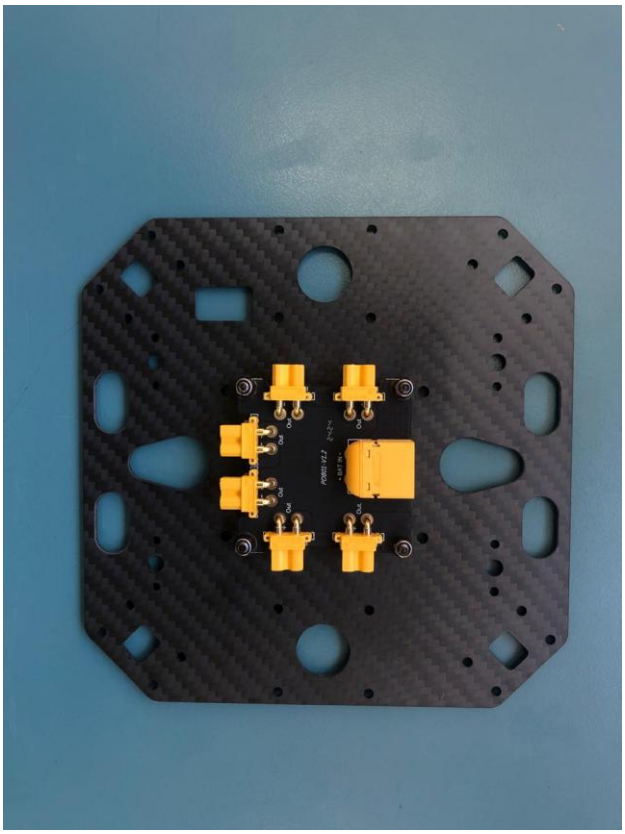
Connect the battery holder plate and the companion computer holder plate using the tubes.

Mount this assembly to the bottom plate of the main chassis with the provided screws.



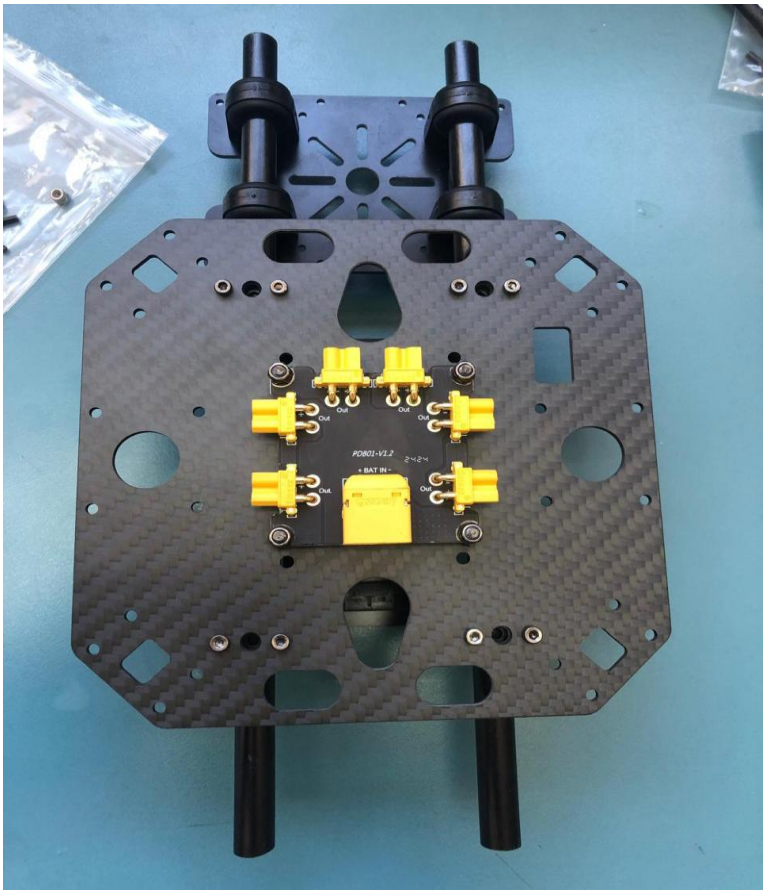
Step 2: Mount the Power Distribution Module

Fix the power distribution module onto the bottom plate.



Step 3: Connecting Holder to the Bottom Plate

Mount the holder assembly to the bottom plate of the main chassis.

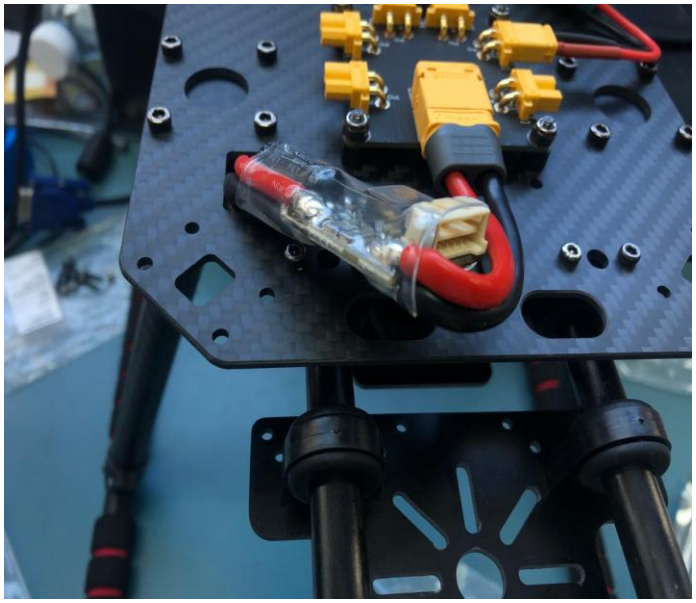


Step 4: Assemble and Mount the Landing Gears

1. Connect the vertical landing gear parts to the horizontal cross bars to form a single landing gear assembly.
2. Mount this complete landing gear assembly to the bottom plate of the chassis.

Step 5: Route the Power Module

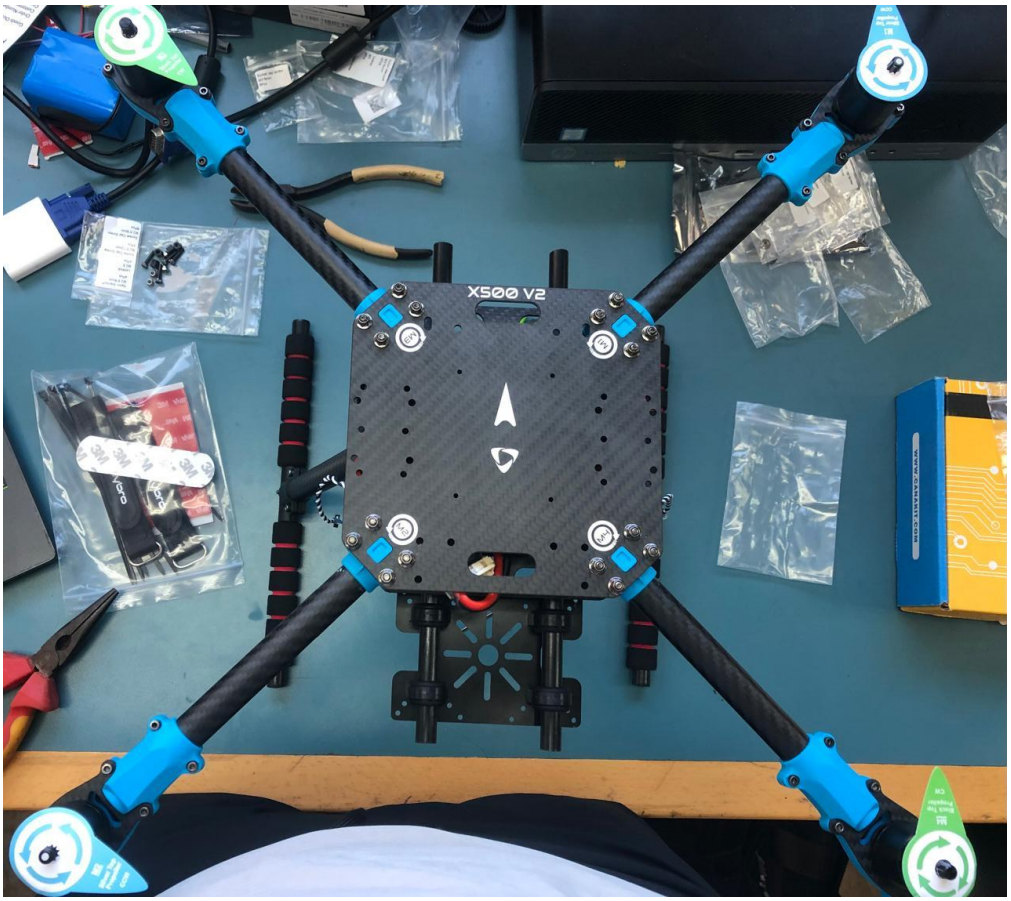
1. Pass the power module through the rectangular opening in the bottom plate.
2. Connect one end of the power module to the BAT ± port of the power distribution module.
3. Leave the other end pointing downward so it can be connected to the battery later.



Step 6: Install the Arms and Motors

1. Connect the arms between the bottom plate and top plate of the body frame.
2. Ensure each arm is positioned correctly according to the top plate arrow:
    a. Motor 1: right front (above)
    b. Motor 2: left rear (below) → forms diagonal with Motor 1
    c. Motor 3: left front (above)
    d. Motor 4: right rear (below) → forms diagonal with Motor 3

    This arrangement creates the X shape of the quadcopter.
3. Plug each motor power connector into its corresponding port on the power distribution board.



Step 7: Mount the Pixhawk Autopilot

1. Place the Pixhawk autopilot at the center of the top plate of the main body frame using double tape.
2. Align the arrow on the Pixhawk with the arrow on the top plate to ensure correct orientation.

Step 8: Mount the GPS Module

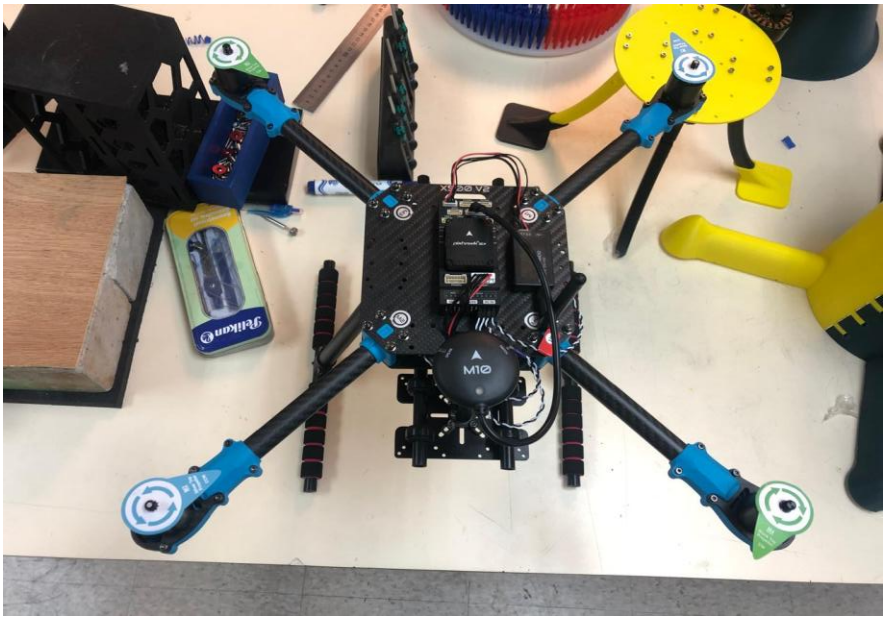
Place the GPS module on the companion computer's holder using screws if its standoff is long to keep it higher than the autopilot enough, otherwise mount it on the top plate next to the Pixhawk autopilot using screws.

Step 9: Mount the Telemetry Module

Place the telemetry module on the top plate, on the other side of the Pixhawk autopilot using double tape.

Step 10: Connect Modules to Pixhawk

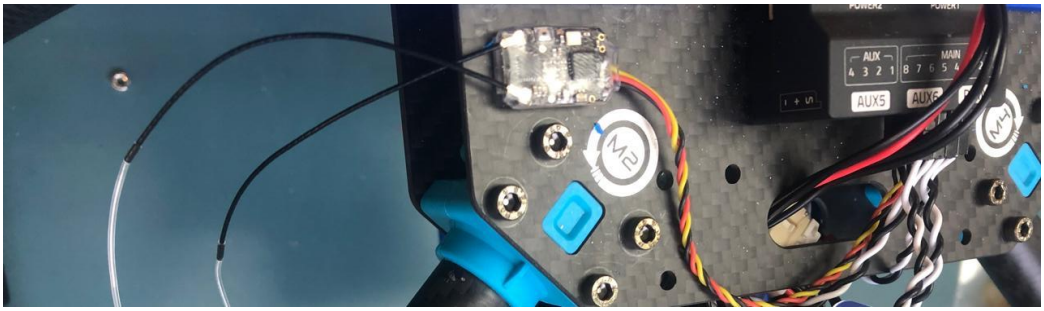
1. Plug the GPS module into its designated GPS port on the Pixhawk.
2. Plug the telemetry module into its specific telemetry port.



Step 11: Place the Receiver Module

Position the receiver module on the top plate of the main body frame using double tape.

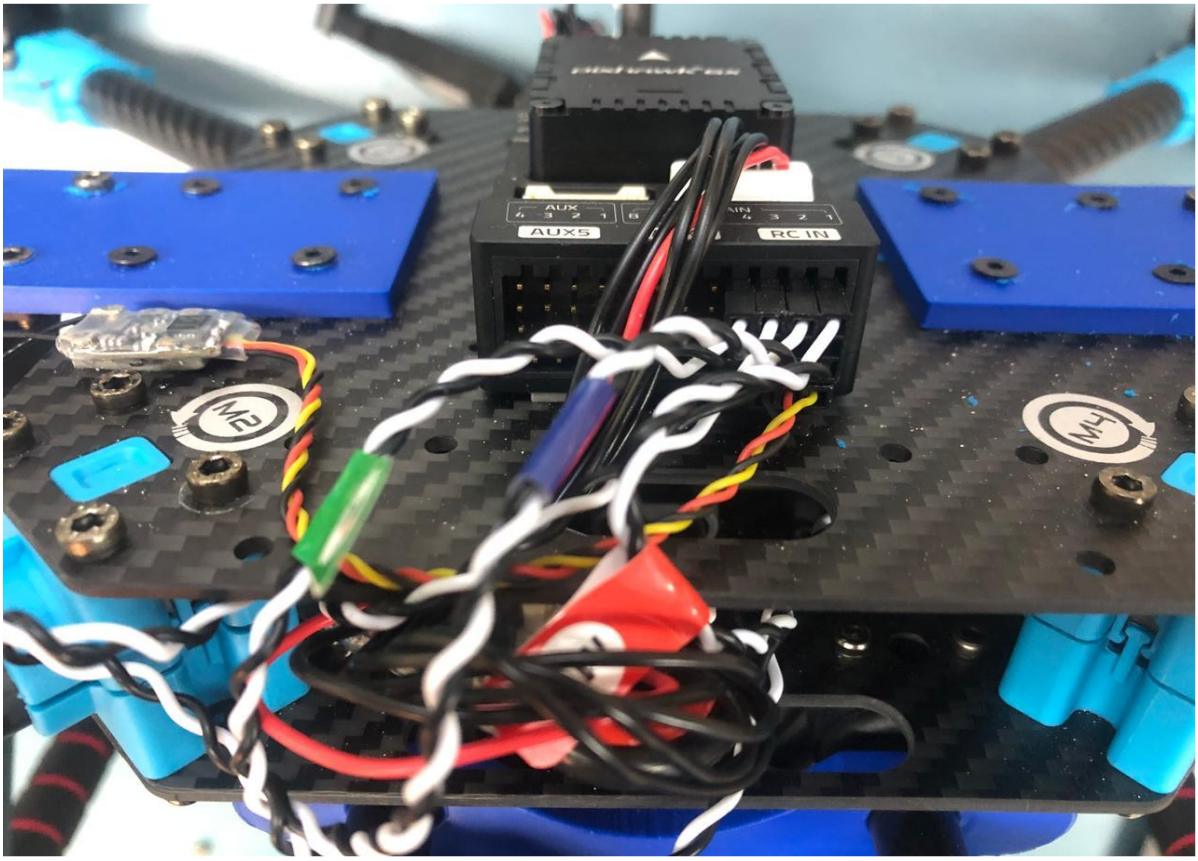
Note that wires shall be connected to the RC IN port in the autopilot, it is 3 pins in a horizontal row, where ground pin is to the left of this row.



Step 12: Connect Motor Signal Wires

Plug each motor signal wire into the corresponding motor output pins on the Pixhawk:

a. M1 → Motor 1
b. M2 → Motor 2
c. M3 → Motor 3
d. M4 → Motor 4



Steps for binding the RC with the receiver

- Press and hold the BIND button on the receiver then connect power. After approximately 3 seconds, the receiver LED will be RED, the receiver is now in bind mode.

- Select the D8 protocol for the multi-protocol menu of your remote control, and press the [BIND] option, the red light of the receiver will flash indicating successful bind.

- Exit bind mode on your remote control and disconnect power to the receiver then power the receiver once more. The LED will now be solid RED indicated the bind is now done. If not please repeat step 1 and 2.

  * Doesn’t support frsky transmitter, only for MPM radio.