Set up

Connect APM to computer

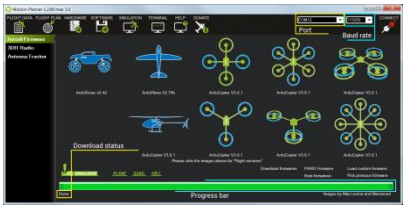
Once you've downloaded Mission Planner onto your ground station computer, connect APM to your computer using the micro USB connector and APM's micro USB port.

Connect APM to Mission Planner

Next we'll let Mission Planner know which port we're using to connect to APM. In Mission Planner, use the drop-down menus in the upper-right corner of the screen (near the Connect button) to connect to APM. Select **Arduino Mega 2560** and set the Baud rate to **115200** as shown. Don't hit **Connect** just yet.

Select firmware

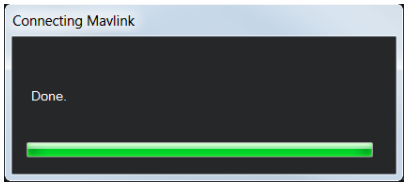
Now we'll select which firmware to download to APM; this depends on the configuration of your craft. Select the Hardware screen from the icons at the top of the display. Choose your copter's frame by clicking the corresponding icon: Quad, Hexa, Y6, plane, rover, or other. (We'll specify + or x configuration later.) The firmware screen will not appear if you have already selected Connect, so ensure that Mission Planner shows a disconnected icon in the upper-right corner to access the firmware.



Once you select your frame, Mission Planner will automatically detect the latest firmware version for your craft and prompt you to confirm the download. Select **Yes** to download the firmware onto APM. When the download status reads **Done**, your firmware download is complete.

Connect to MavLink

Select **Connect** (upper-right corner of the screen) to load MavLink parameters to APM. Mission Planner will display a window showing the progress of the MavLink download.



When the window displays **Done** and Mission Planner shows the **Disconnect** option in place of Connect, your APM firmware has been downloaded successfully.

	Select **Connect** to load MavLink parameters.
	Once connected, Mission Planner displays the **Disconnect** option.