Bind drone (SR24) to ST16



On ST16 we create a new model, type is Typhoon H. Call it "My Thunderbird" or whatever you want.

The bind process for camera CGO3+ is as usual.

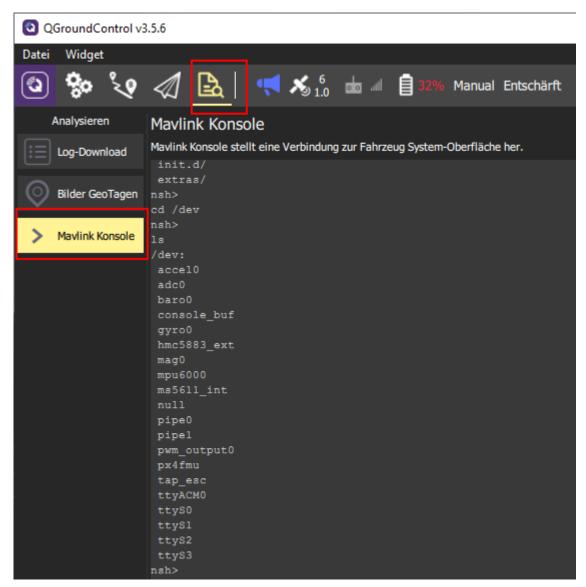
To bind the 2.4GHz receiver the drone must be in bind mode. This is no more possible by lift the back end of the copter.

We have to use QGroundControl (aka QGC). Connect the drone tp QGC by USB cable.

Go to Mavlink console. This is a nice tool. We can see a lot interesting here, i.e. the hardware driver:

cd /dev

ls



free

But hey, we want to set the Thunderbird into bind-mode! Type:

typhoon bind start

Mavlink C		. the colinte	EJECT POSITION CONTROL					
Mavlink Console provides a connection to the vehicle's system								
NuttShell (NSH) nsh> help								
help usage: help [-v] [<cmd>]</cmd>								
[? break cat cd	date			mv mw ps		test time true umount unset	usleep	
Builtin Apps: gps ver serdis								
reflect	typh	oon_bind		vmount				
send_eve		_telemetr		sercon				
ist8310		hardfault_log		perf				
config			mc_att_control		sih			
listener		mavl	mavlink		attitude_estimator_q			
rc_input		test	test_ppm		load_mon			
commander		sens	sensors		top			
motor_test			logger		navigator			
tune_control			battery_status		mc_pos_control			
ekf2			_detector		uorb			
mixer			dataman		fmu			
adc	hmc5			pwm				
tap_esc	nsht			ms5611				
mpu6000		para	param		dmesg			
nsh>								
typhoon_bind								
<pre>Usage: typhoon_bind <command/> [arguments] Commands: start</pre>								
>								
typhoon_bind start								
nsh> INFO [typhoon_bind] Bind command sent.								
INFO [typhoon_bind] Please reboot the drone before flight.								

Then go to Bind menu of the ST16 as usual and tap on "Refresh". Select the receiver and tap on "Bind". Done!