

## Bind drone (SR24) to ST16



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

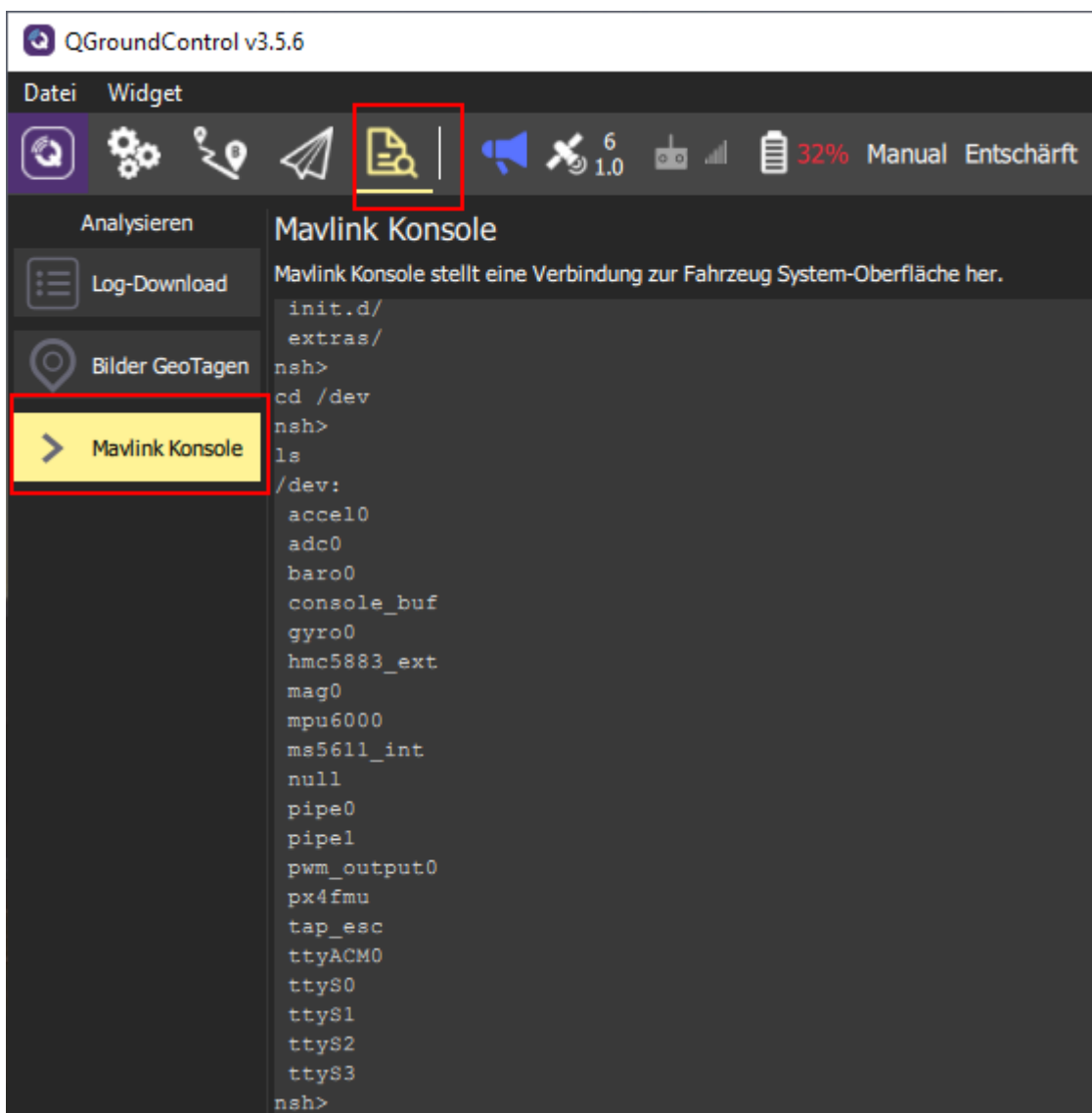
The bind process for camera CGO3+ is as usual.

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 to 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
```



Or how many memory is free/used:

**free**

But hey, we want to bind. Type:

**typhoon\_bind start**

```
Mavlink Console
Mavlink Console provides a connection to the vehicle's system

NuttShell (NSH)
nsh> help
help usage:  help [-v] [<cmd>]

[      cp      exec      help      mount      rm      test      usleep
?      cmp      exit      kill      mv      rmdir      time
break   date     export   ls      mw      set      true
cat     df      false   mkdir   ps      sh      umount
cd      echo     free    mkfatfs pwd     sleep   unset

Builtin Apps:
gps          ver          serdis
reflect      typhoon_bind vmount
send_event   st16_telemetry sercon
ist8310      hardfault_log perf
config       mc_att_control sih
listener     mavlink      attitude_estimator_q
rc_input     test_ppm     load_mon
commander    sensors      top
motor_test   logger       navigator
tune_control battery_status mc_pos_control
ekf2         land_detector uorb
mixer        dataman      fmu
adc          hmc5883      pwm
tap_esc     nshterm      ms5611
mpu6000     param        dmesg

nsh>
typhoon_bind
Usage: typhoon_bind <command> [arguments...]
Commands:

    start
>
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!

