# **Thunderbird**



Eine speziell angepasste Firmware für den Yuneec Typhoon H basierend auf dem PX4 Autopilot von Toni Rosendahl

# **Benutzer Handbuch**

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# Kurzbeschreibung



"**Thunderbird**" ist eine speziell angepasste Firmware für den Yuneec Typhoon H (auch als H480 bekannt) auf der Basis vom **PX4 Autopilot**. Es ist auch ein Synonym für einen Typhoon H, der mit dieser Firmware fliegt.

Mit der Thunderbird Firmware kann man eine Menge der Funktionen vom PX4 Autopilot mit einem normalen Yuneec Typhoon H (H480) in Verbindung mit der ST16 nutzen. An der ST16 wird nichts geändert. Deshalb wird sie in diesem Handbuch auch nicht beschrieben.

Zum Konfigurieren, Kalibrieren und zum Erstellen von Missions brauchen wird das Tool "QGroundControl" (QGC).

QGroundControl allows you to setup and tune all parameters of the drone, but allows you also to do the wrong things. You should know what you do if you touch the parameters or settings.

The firmware was invented and developed by **Toni Rosendahl**.

First appearance (with a funny headline) was here: <a href="https://yuneecpilots.com/threads/typhoon-h-480-px4-v1-10-stability-issues.18205">https://yuneecpilots.com/threads/typhoon-h-480-px4-v1-10-stability-issues.18205</a>

The whole project can be found at github: <a href="https://github.com/tonirosendahl/Thunderbird">https://github.com/tonirosendahl/Thunderbird</a> Discover more about PX4 Autopilot: <a href="https://docs.px4.io/">https://docs.px4.io/</a>

The firmware is Open Source. **Please join the community and contribute!** 

#### **Wichtiger Hinweis:**

**You are responsible** for all what you do. So, do only something if you know what you do.

Lies bitte folgende Beschreibungen:

- PX4 Autopilot: <a href="https://docs.px4.io/master/en/index.html">https://docs.px4.io/master/en/index.html</a>
 - QGroundControl: <a href="https://docs.ggroundcontrol.com/en/">https://docs.ggroundcontrol.com/en/</a>

Operate Thunderbird in open area, away from people, vehicles and property. **Always be careful in what you do.** 

§ Bitte beachte die in deinem Land gültigen Regeln und Gesetze.

# First steps

You have a complete new drone with different behavior compared to stock Typhoon H.

Get familiar with it and learn to fly the new drone. Be careful at the beginning, start in open and free area. Keep it away from trees.

You do not have to do anything on ST16 side. Stock settings there are OK.

It is highly recommended to read how to operate the PX4.

https://docs.px4.io/master/en/flying/

#### Power on/off

To power-on the drone hold the power button down for more than 8sec until the status-LED and LEDs on motor arms are on.

The drone keeps silence, it plays no sound.

To power-off the drone remove the battery. Powering off is currently not possible by power button.

# **Arming/disarming**

Arming and disarming requires the **speed selector to be in FAST (rabbit) mode**.

The well known red button on the ST16 does NOT arm or disarm the drone. We need a CSC command: Hold the throttle stick in the bottom right corner until motors starting.

#### **Important note:**

Tough it is not very likely the above described CSC command may disarm the drone when hold the bottom right position of the throttle stick too long. To spiral down right is not a good idea to bring the drone down.

# **Flying**

In default settings, the top position of the flight mode switch is Stabilize/Manual (same as Typhoon H with switched-off GPS), middle position is Position mode (Typhoon with the GPS aka Angle mode) and bottom one is RTH.

Mission, Acro or Rattitude modes are not there by default. Be careful with Acro or Rattitude mode!

Flight modes can be assigned to switches by using channel settings and also by switch assignment in QGroundControl or in combination of both.

Compared to stock Typhoon H you have to pay attention to following:

- In Position mode, the Thunderbird flies smoother. This is fine but you need more room because the "break path" is a bit longer than expected.
- In Stability mode, you have to maintain the altitude by yourself. Throttle stick means thrust in this case. If you pull the stick fully down, the Thunderbird comes down and I mean really down like a free falling stone.
- In all non-GNSS-assisted flight modes forget the ST16 screen. Keep both eyes on the drone.
- The Thunderbird is no race drone! Keep in mind that its weight is ~2kg and it is fast. There is no such thing like FPV available due to latency of the video downlink.

#### **Important note:**

The ST16 is not monitoring the voltage. It waits on the Voltage Warning Flags that never come from Thunderbird. **All pilots should be aware about that and monitor the voltage by themselves.** Don't drain the battery down to the minimum capacity. It is better to be conservative and bring it home with enough fuel in the tank.

At BAT\_EMERGEN\_THR (Default 7%) it will raise fail-save and land wherever it is without prior warning.

# Sensor calibrations and settings

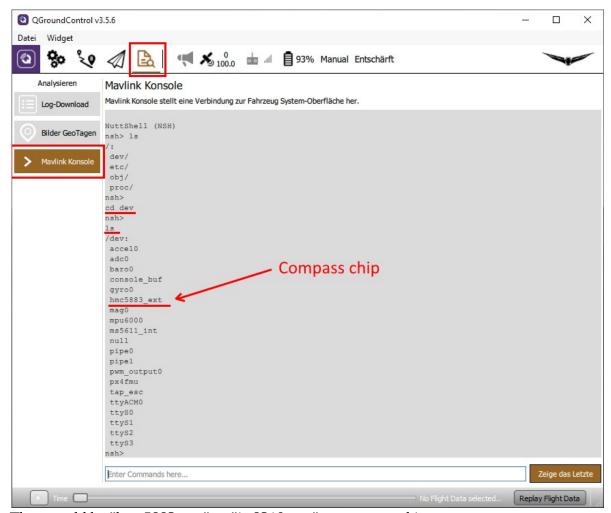
Sensor calibrations can only be done by QGroundControl. Connect the drone to QGC by long, flexible USB cable.

After changes changes, repairs and parameter file upload you need to check compass orientation and do a complete calibration.

# **Compass orientation settings**

For Typhoon H exists two different compass chips. Older GPS boards have HMC5883, newer boards have IST8310 applied as compass chip (magnetometer). To find out which one you have, connect the drone to QGC and go to Mavlink console:

Type: **cd /dev** then **ls** and you will get a list of drivers for the hardware.



There could be "hmc5883\_ext" or "ist8310\_ext" as compass chip.

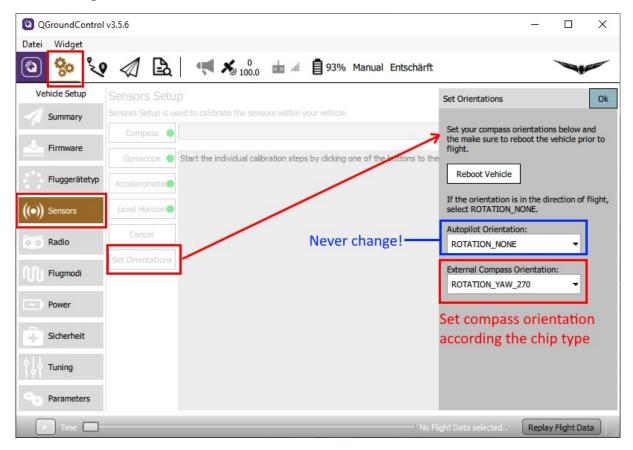
**Note:** If not all sensors are listed disconnect and reconnect to update the list.

**Important:** If you have the "hmc5883\_ext", you have to change External Compass Orientation to "ROTATION YAW 270".

For "ist8310\_ext" it must be "ROTATION\_YAW\_180".

Never change Autopilot orientation. It must be kept at "ROTATION\_NONE".

Go to Settings > Sensors > Set Orientation



Then set External Compass Orientation to the correct value depending on you compass hardware. Save with "OK" and reboot the Thunderbird.

After changes do at least a compass calibration.

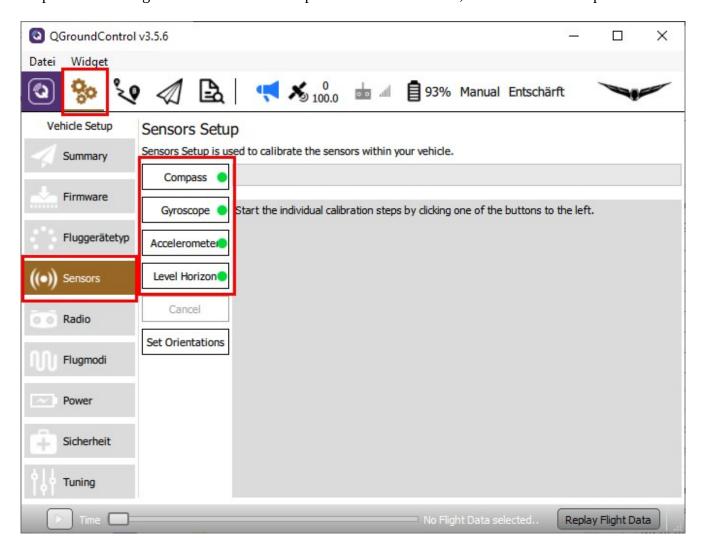
Read more: <a href="https://docs.ggroundcontrol.com/en/SetupView/SetupView.html">https://docs.ggroundcontrol.com/en/SetupView.html</a>

### Calibration

Remove the camera.

Go to Settings > Sensors and follow the instructions on the screen for Compass, Gyroscope, Accelerometer and Level Horizon. **Do not try to calibrate ESC's.** It will not work and is not required.

Prepare some fitting wooden blocks that keep the drone in backward, forward and lateral positions.



Learn more: <a href="https://docs.qgroundcontrol.com/en/SetupView/sensors">https://docs.qgroundcontrol.com/en/SetupView/sensors</a> px4.html

Currently there is no "wireless" way to calibrate. **Be careful with the cable.** Best use a longer micro USB data cable.

# ST16 mit dem Empfänger SR24 im Kopter binden

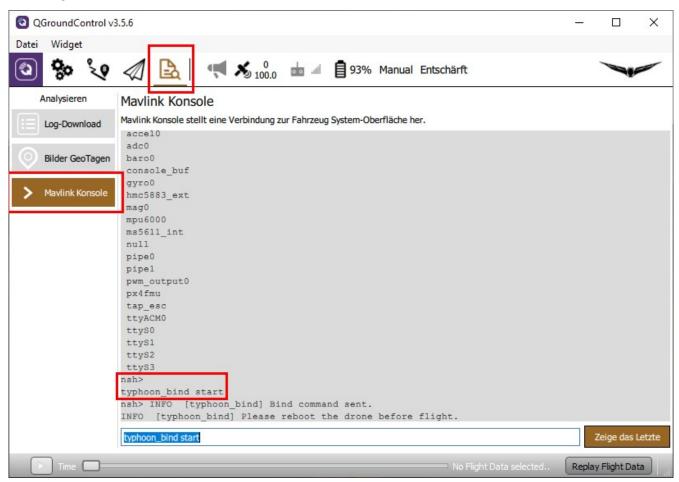
Wir legen uns zuerst auf der ST16 für den Thunderbird ein neues Modell an. Dieses Binden wir dann mit Kopter und Kamera. Bindeprozess für die Kamera CGO3+ funktioniert wie gehabt.

Um den Empfänger im Kopter zu binden, muss der Kopter in den Bindemodus versetzt werden. Dazu muss man den Kopter per USB-Kabel mit dem PC verbinden und QGroundControl starten. Dort in die PX4 Konsole aufrufen:

Icon Log-Auswertung > Mavlink Konsole.

Man kann sich hier schon allerlei ansehen, zum Beispiel, welche Geräte im Kopter vorhanden sind.

cd /dev ls



Aber das nur nebenbei. Eigentlich wollten wir den Kopter in den Bindemodus bringen. Dazu an der Konsole folgendes eingeben:

typhoon bind start

Dann auf der ST16 ins Bindemenü gehen, wie gewohnt auf "Refresh" tippen und den angezeigten Empfänger wie üblich binden. Fertig.

# **Drone flight modes**

## **Startup**

#### Initialization

The GNSS and navigation systems are not ready. The home position is not set.

The drone can be forced to fly in non-GNSS modes but RTH will not be available during that flight. GNSS-assisted flight modes are degraded to "Stabilize" with or without altitude hold. The GNSS-assisted modes will become available when the GNSS and estimator become ready. This will happen also during flight, but the RTH remains inoperable until you land and take-off again, as there is no home position set for this flight. The drone takes a minute or two to start up, to be fully mission capable. This never happens indoors, but it is perfectly flyable there.

Status LED: **GREEN blinking**. The ST16 shows "Acquiring" in GPS mode display and "Start" as a flight mode.

#### Ready

The drone is ready. It has full navigation capability and home position is set. Status LED: **GREEN solid**. ST16 GPS status changes from "Acquiring" to "Ready" and flight mode display shows also "Ready". You are good to go, no need to wait any further.

# **GNSS** assisted flight modes

#### Mission mode

The Thunderbird is fully automatic. This is the automated flight mode and easiest of them all since the drone flies itself from take-off to motor shutdown.

Status LED: PURPLE blinking, ST16 flight mode display: "Waypoint".

#### Position mode

The Thunderbird flies like a stock Typhoon in Angle Mode. Status LED: **PURPLE solid**, ST16 flight mode display: "Angle".

*Note:* All sensors and GNSS must be fully operational and perfectly calibrated for these modes.

# Stabilized flight modes

#### Altitude mode

Stabilized mode with altitude hold and assisted throttle. Auto-throttle is active, throttle stick controls altitude.

The Thunderbird flies like a stock Typhoon in Angle Mode without GPS.

Status LED: **BLUE blinking**.

#### Stabilize mode

Throttle controls altitude. The Thunderbird controls thrust to maintain the altitude. If the Position mode was requested with no valid positioning solution, meaning you took off before the estimator and GNSS were ready, this is what you will get instead as a fallback.

This flight mode is not mapped to the mode selector switch by default at the standard parameter settings. But you can summon this by requesting a position mode from a drone that took off before it was ready. Same as "Stability" mode, known from Blade Chroma or Blade 350QX.

Status LED: **BLUE solid**, ST16 flight mode display: "THR".

*Note:* These modes do not require GPS magnetometer being operational. Indoor flight is possible and magnetic interference are no issue. These modes can be used to recover the drone from GPS/magnetometer issues, if you'll ever encounter any. These modes require active controlling and visual line of sight, but they are still rather easy to fly.

# Manual flight modes

#### Rattitude mode

"Assisted Acrobatics" enabled. Release the sticks and the drone *should* self-recover if there is enough altitude.

Status LED: WHITE purple blinking, ST16 flight mode display: "Rate".

### Manual, Acro or Rate mode

Sticks control angular acceleration, no self-leveling, no braking, direct thrust control, absolutely zero assistance from the drone. The GPS, magnetometer, barometer and accelerometer are sleeping, only the gyro data is used. You are in control now.

Same as "Agility" mode, known from Blade Chroma or Blade 350QX.

Status LED: WHITE solid, ST16 flight mode display: "Rate".

*Note:* These modes are **not set** to the mode selector switch in my default parameter file. You have to enable these by yourself. The "Purple solid" is a **very difficult mode** to fly, but allows you do anything with the drone.

### Fail-safe mode

Fail-safes are activated (RTH) or the drone attempts auto-land with a failed GPS. Status LED: **RED blinking.** 

## **Drone status LED codes**

## Drone status LED basic rules, regardless of color coding

- 1. When the LED is SOLID regardless of color, you have the full control.
- 2. When the LED is BLINKING, the Thunderbird is actively doing something (like assisting you somehow).
- 3. Than lighter the color, than more challenging and rewarding is it to fly.
- 4. Red light means malfunction, fail-safe mode or manual requested RTH.

#### **RGB** status LED details

#### **Green: Startup**

**GREEN blinking:** The GNSS and navigation systems are not ready and home position is not set. The ST16 shows "Acquiring" in GPS mode display and "Start" as a flight mode. **GREEN solid:** The drone is **ready**. The green light will not appear when the drone is airborne. ST16 GPS status changes from "Acquiring" to "Ready" and flight mode display shows also "Ready". You are good to go, no need to wait any further.

#### **Purple: GNSS-assisted flight**

**PURPLE blinking: Mission mode.** ST16 flight mode display: "Waypoint". **PURPLE solid: Position mode.** ST16 flight mode display: "Angle".

#### **Blue: Stabilized flight**

**BLUE blinking: Altitude mode** 

**BLUE solid: Stabilize mode.** ST16 flight mode display: "THR".

#### White: Manual flight modes

**WHITE** purple blinking: Rattitude mode or "Assisted Acrobatics".

ST16 flight mode display: "Rate".

WHITE **solid:** Manual, Acro or Rate mode. ST16 flight mode display: "Rate" (not tested yet).

#### Red: Fail-safe, RTH, malfunction

**RED blinking:** The drone has degraded performance, but is airborne, still operational and attempts an automatic recovery. The LED blinks red when the fail-safes are activated (RTH) or the drone attempts auto-land with a failed GPS. It may change between red and previous color code for some time. However, it is recommended to bring it home at this point.

**RED solid:** Malfunction, arming is prohibited. ST16 flight mode display: "EMER".

# **Parameter settings**

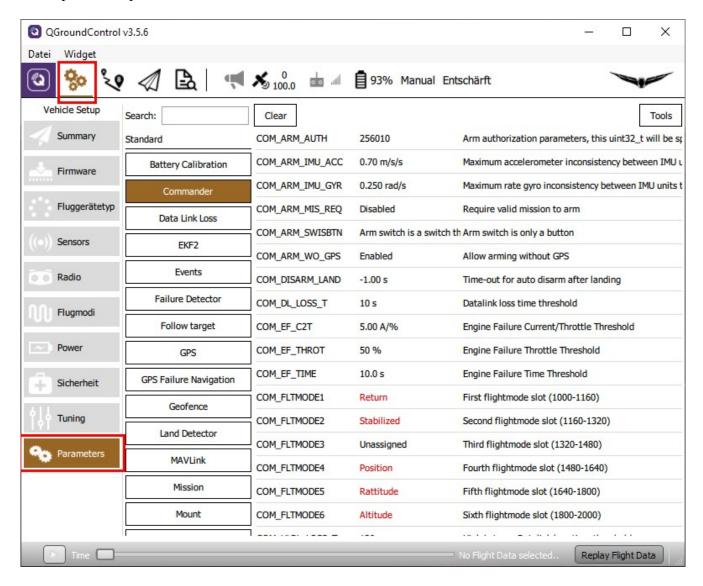
Parameter settings needs to be done with QGroundControl. Changed parameters are **not** stored in the model on ST16.

It is recommended to store last working parameter set into a file before you change something. Make a note what parameter you have changes and why (see Parameter change sheet at the end of this document). The stored parameter file is a backup and can be used to restore the whole parameter set in case of problems.

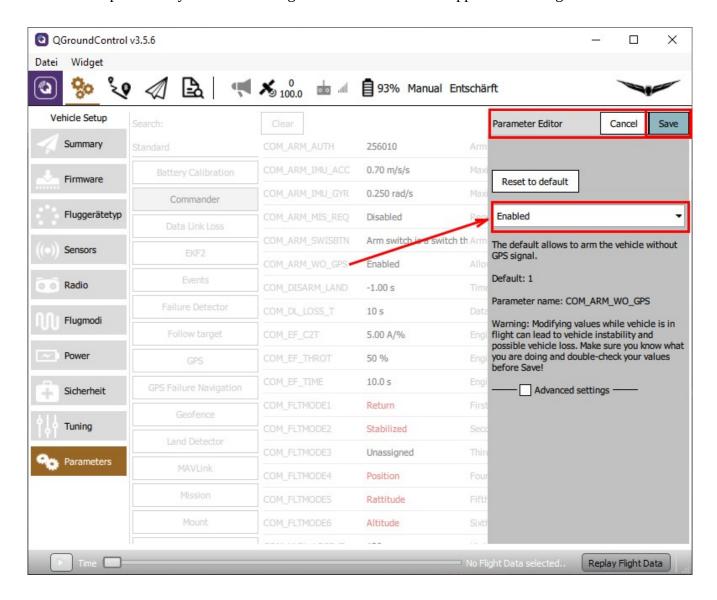
# Change parameters

Power up the drone and connect it via USB to QGroundControl.

Go to Settings (icon with gearwheels) > Parameters. Parameter sets are grouped by its functionality. To find a parameter you can use the search function.



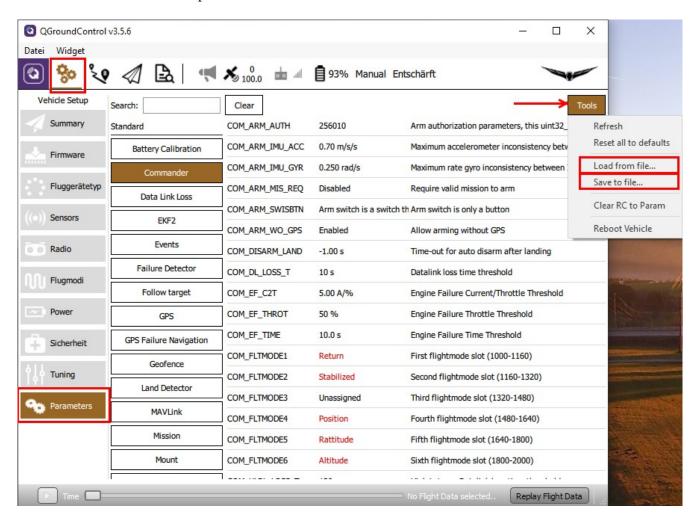
Click on the parameter you want to change. The Parameter editor appears on the right.



Change parameter (select from list or enter value) and Save. Some parameters require reboot of the drone.

## Save parameter sets

Go to Settings (icon with gearwheels) > Parameters > Tools > Save to file... Enter useful path and filename to remember what parameter set it was and save it.



# Parameter von Datei laden

The parameter file from the last working configuration can be used to restore parameter settings in case of problems with the new one.

Go to Settings (icon with gearwheels) > Parameters > Tools > Load from file... Select parameter file with last working settings and upload it to the drone. Reboot the drone.

Check Compass orientation depending on compass chip and do proper calibration.

# Firmware Update Prozedur für Ubuntu LINUX

Folgende Dateien in ein eigenes Verzeichnis kopieren:

```
flash_typhoon_bootloader
px_uploader.py
yuneec_typhoon_h.fw (Beispielhafter Dateiname für die Firmware)
```

Mit folgenden Befehlen kann man feststellen, welcher Port benutzt wird. USB-Kabel ab- und wieder anstecken.

```
dmesg | grep usb
dmesg | grep tty
```

Mit dem ersten Befehl sieht man, welche USB-Geräte als letztes erkannt wurden. Mit dem zweiten Befehl sieht man die Reaktion des entsprechenden tty-Ports mit gleichem Zeitstempel.

```
♣ he@SSD256 ~
                                                                                            X
PS/2 Optical Mouse] on usb-0000:00:la.0-1.4.4/input0
     5.877427] usbcore: registered new interface driver btusb
     5.988457] input: HP Webcam [2 MP Macro]: HP Webc as /devices/pci0000:00/0000:00:la.0/usb]
1/1-1.5/1-1.5:1.0/input/input20
    5.988562] usbcore: registered new interface driver uvcvideo
     6.045226] audit: type=1400 audit(1577738889.496:9): apparmor="STATUS" operation="profile
d" profile="unconfined" name="/usr/sbin/ipp<mark>usbx</mark>d" pid=755 comm="apparmor parser"
   162.227296] usb 2-1.4: new full-speed USB device number 3 using ehci-pci
   162.338320] usb 2-1.4: New USB device found, idVendor=0001, idProduct=0480
  162.338325] usb 2-1.4: New USB device strings: Mfr=1, Product=2, SerialNumber=3
  162.338328] usb 2-1.4: Product: TyphoonH Bootloader
  162.338331] usb 2-1.4: Manufacturer: PX4 AP
  162.338334] usb 2-1.4: SerialNumber: 0
  162.367625] usbcore: registered new interface driver cdc acm
  171.061725] usb 2-1.4: USB disconnect, device number 3
  171.283316] usb 2-1.4: new full-speed USB device number 4 using ehci-pci
  171.397945] usb 2-1.4: New USB device found, idVendor=26ac, idProduct=0001
  171.397950] usb 2-1.4: New USB device strings: Mfr=1, Product=2, SerialNumber=3
  171.397953] usb 2-1.4: Product: PX4 Typhoon H -
  171.397956] usb 2-1.4: Manufacturer: Yuneec
  171.397959] usb 2-1.4: SerialNumber: 0
he@SSD256 ~ $ dmesg | grep tty
     0.000000] console [tty0] enabled
     1.531997] 00:04: ttyS0 at I/O 0x3f8 (irq = 4, base baud = 115200) is a 16550A
   1.554576] 0000:00:16.3: ttyS4 at I/O 0x6050 (irq = 17, base_baud = 115200) is a 16550A 162.366799] cdc_acm 2-1.4:1.0: ttyACM0: USB ACM device number3 bootloader assigned
   171.398678] cdc acm 2-1.4:1.0: ttyACMO: USB ACM device
ne@SSD256 ~ $
```

Der gesuchte Port ist hier "ttyACM0".

Was man auch sieht, dass nach dem Einschalten der Bootloader startet und danach die Autopilot Software. Wenn der Autopilot bereits gestartet ist, kann man nicht mehr Flashen. Deshalb ist es wichtig, das Script zum Flashen zu starten, wenn das MCU-Board noch stromlos ist. Es wird erst nach dem Anstecken des USB-Kabels mit Strom versorgt und dann erwischen wir den Bootloader.

# **Autopilot Flashen**

Nun können wir die Datei "flash\_typhoon\_bootloader" editieren, um den Port einzustellen. Der Dateiinhalt sollte dann so aussehen:

```
python px_uploader.py --port /dev/ttyACMO --force yuneec_typhoon_h.fw
```

Ein Terminal öffnen. In das Verzeichnis wechseln, wo man die drei Dateien hineinkopiert hat und die Scripte ausführbar machen.

```
chmod +x ./flash_typhoon_bootloader
chmod +x ./px_uploader.py
```

Sicherstellen, dass USB Verbindung zum Kopter **getrennt** ist und **keine** Batterie im Kopter ist (MCU-Board stromlos). Die Stromversorgung des MCU-Boards kommt dann über USB.

Update Prozess starten:

```
./flash typhoon bootloader
```

Sofort danach die USB Verbindung zum Kopter herstellen. Warten, bis es losgeht und den Updateprozess beobachten.

```
he@SSD256 ~/tmp/Thunderbird_19122019_FT
                                                                         ×
he@SSD256 ~ $ cd tmp
he@SSD256 ~/tmp $ 1s
info.txt Thunderbird 19122019 FT
he@SSD256 ~/tmp $ cd Thunderbird 19122019 FT/
he@SSD256 ~/tmp/Thunderbird_19122019_FT $ ls
flash_typhoon_bootloader _yuneec_typhoon_h.bin
px_uploader.py yuneec_typhoon_h.fw
he@SSD256 ~/tmp/Thunderbird_19122019_FT $ ./flash_typhoon_bootloader
Loaded firmware for board id: 42,1 size: 985500 bytes (98.55%), waiting for the
bootloader...
Attempting reboot on /dev/ttyACMO with baudrate=57600...
If the board does not respond, unplug and re-plug the USB connector.
Attempting reboot on /dev/ttyACMO with baudrate=57600...
If the board does not respond, unplug and re-plug the USB connector.
Found board id: 42,0 bootloader version: 5 on /dev/ttyACM0
sn: 0027001f3335511135363336
chip: 10076413
family: STM32F40x
revision: 1
flash: 1015808 bytes
Windowed mode: False
Erase : [========] 100.0%
Program: [========] 100.0%
Verify : [========] 100.0%
Rebooting. Elapsed Time 17.667
he@SSD256 ~/tmp/Thunderbird 19122019 FT $
```

Kopter nach erfolgreichen Flash-Vorgang neu starten.

Danach unbedingt alles prüfen und **kalibrieren** wie für einen neuen Kopter üblich.

# Firmware Update Prozedur für Windows

## **Preparation**

Copy following files in an own directory:

```
flash_typhoon_bootloader
px_uploader.py
yuneec typhoon h.fw
```

Start script Flash utility The firmware itself

△The file name for the firmware may change. "yuneec typhoon h.fw" is used here as example.

Install Python for Windows if not yet done:

```
Windows key + R to open command field. Type cmd
```

The Windows terminal will be opened. Keep it open, we need it all the time.

```
Type python
```

The Windows Store will be opened and offer Python installation. Follow the instructions to install Python.

If Python is correctly installed it should come up with its own command line >>>.

```
C:\WINDOWS\system32\cmd.exe

C:\Users\he>python

Python 3.7.6 (tags/v3.7.6:43364a7ae0, Dec 19 2019, 01:54:44) [MSC v.1916 64 bit (AMD6 4)] on win32

Type "help", "copyright", "credits" or "license" for more information.

>>> exit()

C:\Users\he>d:
```

Leave it with exit().

Then download module 'serial' for Python:: <a href="https://pypi.org/project/pyserial/#files">https://pypi.org/project/pyserial/#files</a>

File name is "pyserial-3.4-py2.py3-none-any.whl", double click on it to install.

Python is installed now and we can run Python scripts like "px\_uploader.py".

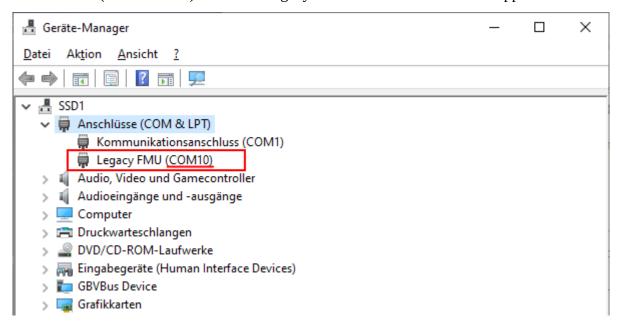
## Find serial port

To find out what TTY port is used by the drone you have to check the Device Manager.

Windows key + R to open command field.

Type devmgmt.msc

The Device Manager will appear. Plug-in the USB cable to connect the drone with the PC. In node "Connections (COM & LPT)" an item "Legacy FMU" with a COM number appears.



Here we found, the port is "COM10".

Now we edit the file "flash\_typhoon\_bootloader" to set the correct port and save it as "flash\_typhoon\_bootloader.bat" to make it executable. The file text should look like that: python px\_uploader.py --port COM10 --force "yuneec\_typhoon\_h.fw"

# **Flashing**

**Note:** After power-on the bootloader starts first and after a while the flight controller starts. If flight controller is running we cannot flash anymore. This is the reason why we have to start the script for flashing prior to power-up the MCU board which is powered by flight battery. If we plug-in the USB cable when the script is already running we will be able to catch the bootloader.

### ▲Make sure the USB connection is cut. (MCU-board powered off).

Start firmware update script:

```
flash_typhoon_bootloader.bat
```

Plug in the USB cable. Then hold the start button of the aircraft down until flashing is complete, disconnect and connect USB cable again. Wait and observe terminal output. Update process will start soon ...

```
C:\WINDOWS\system32\cmd.exe
                                                                                        X
C:\Users\he>python
Python 3.7.6 (tags/v3.7.6:43364a7ae0, Dec 19 2019, 01:54:44) [MSC v.1916 64 bit (AMD64)] on wi
Type "help", "copyright", "credits" or "license" for more information.
>>> exit()
C:\Users\he>D:
D:\>cd temp\tmp
D:\temp\tmp>dir
Datenträger in Laufwerk D: ist Daten
Volumeseriennummer: ECFC-D1D0
Verzeichnis von D:\temp\tmp
01.01.2020 22:29
                    <DIR>
                    <DIR>
01.01.2020 22:29
                                135 flash typhoon bootloader.bat
31.12.2019 14:14
15.12.2019 19:47
                           37.478 px_uploader.py
01.01.2020 22:25
                           193.717 pyserial-3.4-py2.py3-none-any.whl
30.12.2019 16:33
                           796.268 yuneec_typhoon_h.fw
              4 Datei(en),
                                1.027.598 Bytes
              2 Verzeichnis(se), 608.017.375.232 Bytes frei
D:\temp\tmp>flash_typhoon_bootloader.bat
D:\temp\tmp>python px_uploader.py --port COM10 --force yuneec typhoon h.fw
Loaded firmware for board id: 42,1 size: 985500 bytes (98.55%), waiting for the bootloader...
```

Kopter nach erfolgreichen Flash-Vorgang neu starten.

Danach unbedingt alles prüfen und **kalibrieren** wie für einen neuen Kopter üblich.

# **Anhang**

# **Empfohlene Parameter**

Parameter reference: <a href="https://docs.px4.io/v1.9.0/en/advanced">https://docs.px4.io/v1.9.0/en/advanced</a> config/parameter reference.html

Parameter	von	nach	Beschreibung
MPC_Z_VEL_MAX_DN	1.000	3.000	Max. Sinkgeschwindigkeit [m/s] wie beim H480
MPC_Z_VEL_MAX_UP	3.0	5.0	Max. Steiggeschwindigkeit [m/s] wie beim H480
MC_RATT_TH	0.80	0.60	Schwellwert für Stability in Rattitude mode [%] für mehr Acro-Anteil für schönere Rollen oder Loopings
COM_ARM_WO_GPS	Disabled (0)	Enabled (1)	Motorstart ohne GPS-Lock möglich. Für Flüge mit GNSS-Unterstützung warte auf dauerhaft grün leuchtende Status-LED.

▲Achtung: Alle Tuning-Maßnahmen und Parameter Einstellungen können das Flugverhalten beeinflussen und ein Sicherheitsrisiko bedeuten. Bitte tue es auf eigene Verantwortung und nur wenn du weißt, was du tust.

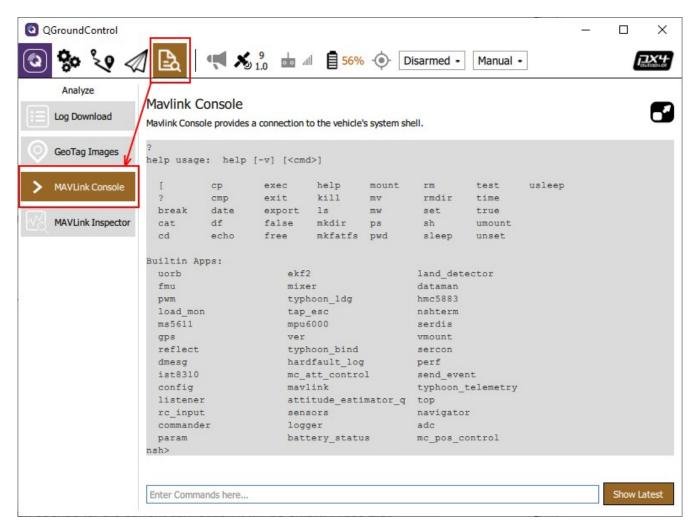
# Some helpful MAVLink Console commands

The MAVLink Console opens a PX4 NSH shell to send commands and receive results when the aircraft is powered on and connected to QGroundControl.

More about the NSH shell: <a href="https://dev.px4.io/v1.9.0/en/debug/system">https://dev.px4.io/v1.9.0/en/debug/system</a> console.html

### Help

? Shows a list of commands and Build-in Apps:



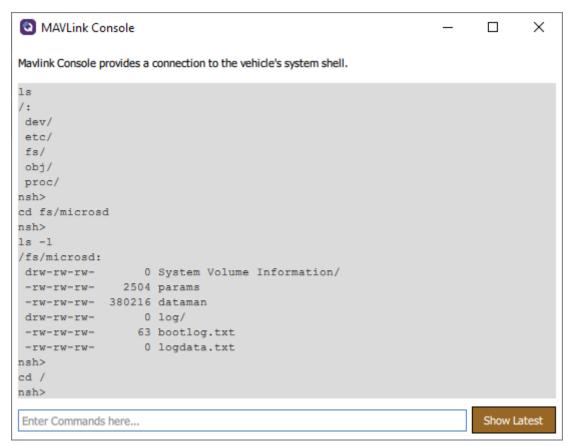
Those shell commands maybe helpful just for information or for troubleshooting. Please execute commands only if you know what you do. Refer to the PX4 Autopilot documentation and QGroundControl manual.

Following commands can be executed without problems, do not change anything and are only used to show some information.

How to use custom command **typhoon bind** please refer to the Thunderbird user manual.

### File system

List files or directories
 cd fs/microsd
 Change directory to list the files on micro SD card
 List the files or directories on micro SD card
 cd /
 Change directory to root directory



With the commands above you can check if you have an SD card inserted and if it is readable.

To download flight logs (ULOG files: \*.ulg) use QGroundControl **Analyze** > **Log Download**. Click on **Refresh** to see updated list of ULOG files.

#### **Devices**

List directories in root diectorycd dev Change directory to 'dev'List devices of the drone

```
MAVLink Console
                                                                       X
Mavlink Console provides a connection to the vehicle's system shell.
nsh>
ls
dev/
etc/
 fs/
obj/
proc/
nsh>
cd dev
nsh>
ls
/dev:
accel0
adc0
baro0
 console_buf
 gyro0
 hmc5883_ext
mag0
mmcsd0
mpu6000
ms5611_int
 null
 pipe0
 pipel
pwm_output0
px4fmu
 tap_esc
 ttyACM0
 ttyS0
 ttyS1
 ttyS2
 ttyS3
nsh>
                                                                       Show Latest
Enter Commands here...
```

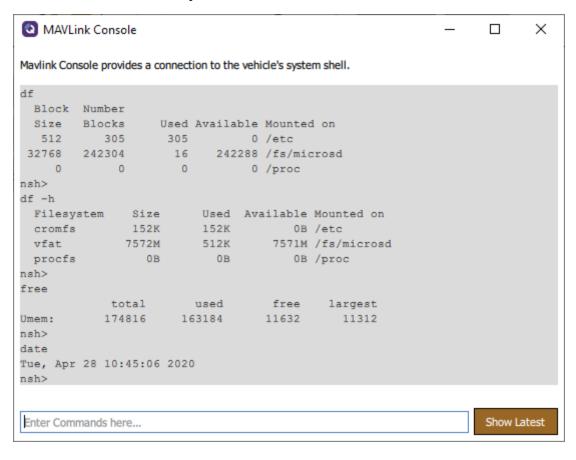
### **System**

**df** Show memory sizes

**df -h** Show memory sizes in 'human readable' format

**free** Show free/used memory

**date** Show system time



# Parameter change sheet



It is recommended to note your parameter settings and its history. Print this sheet.

*Note:* Channel settings on ST16 are stored to the related models. If you want to reset Channel settings, create a new model from scratch.

Parameter settings in QGroundControl are **not** stored in the model on ST16.

Date	Parameter	from	to	Description/reason

### **Cheat sheet**



Proposal for brief description to print it.

Flight mode switch setting (fill table with your own settings)

FlightMode	Switch	Position
Position (Angle mode)	Flight mode switch S4	middle
Altitude (GNSS support off)	Flight mode switch S4	upper
Stabilized (Manual)	Aux switch B2	upper
Rattitude	Aux switch B2	lower
Acro		
Mission		
RTH	Flight mode switch S4	lower

### Power on/off

Power on: Hold power button on drone for 8sec until LEDs are on

**Power off:** remove battery

# **Motor Start / Stop**

Hold throttle stick in the lower right corner

# **Flying**

- ✔ Check location (rules and regulations)
- ✔ Free space for GPS signals, no potential reflectors to avoid multi-path reception
- ✔ Drone battery full, ST16 battery full
- ✔ Check battery voltage during flight