Drone Applications, Components and Assembly
(CSE2040)

Lab Exercise 2:
Drone Assembly

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step 1:

Take the circuit board of the S500 mainboard

Step 2:

Lower the powerboard to make it more sturdy

Step 3:

positive/negative inventor/harden outward

Step 4:

Solidary on the power board uses -ve and +ve cables to sign the solidar with a PLB and create a power cable.

Step 5:

Get a power distribution board and connect one end to the stronger power board cable and the other end to the battery

Step 6:

Take 4 rod holders with M2 5*6 screws and fix them to the main PLB. Secure the rod to the bracket using M384 screws

Step 7:

Take the U-clamp and fix it on the street

Step 8:

Secure the plate to the V-clamp with M2.5-PO 45*5.

Step 9:

Take a small board S500. Take the focus arm forward and fix the rotation with a few screws

Step 10:

Check his 3 lines on the motherboard which is considered the front.

Step 11:

Check the arrow on the plate and attach it to the arm with M2 5*6. Locate the upper right rotor counterclockwise (1) and the upper left rotor clockwise (black (3), left rear (black) (4), right rear (white)).

Step 12:

Fix the boarding legs at the bottom with arms using M2 5*8 screws

Step 13:

Fix the damper shock between two small blocks and fix it with double side tape in the small board

Step 14:

Fix the pixhawk based on the arrow mark placing from the sides

Step 15:

From the power distribution board fix the cable in the power port of the pixhawk

Step 16:

Refer STEP 11 check the rotor position, plugin the position according to the roots members mentioned in STEP 11 1to 4 respective position

Step 17:

Get the remote controller(transmitter)box. Take the F5-i46B receiver. Fix it in the main PLB using double side tape connects the given wire to the pixhawk RC post it to the channel 4,5,6

Step 18:

Take the GPS and mount it in the 2nd position of the vmi use the screws for fixing it in the big pin should be replaced

Step 19:

Fix the buzzer to the 2nd position And Connect It in The Pixhawk

Step 20:

Fix the smart/safety switch in the 4th positive of the and connect it in the Pixhawk

Step 21:

Connect the telemetry in the Pixhawk and fix it in the main board

Step 22:

Take the 300 Amph lithium polymer battery and place it in the bottom using welerow and connect it to the power distribution +ive and -ive