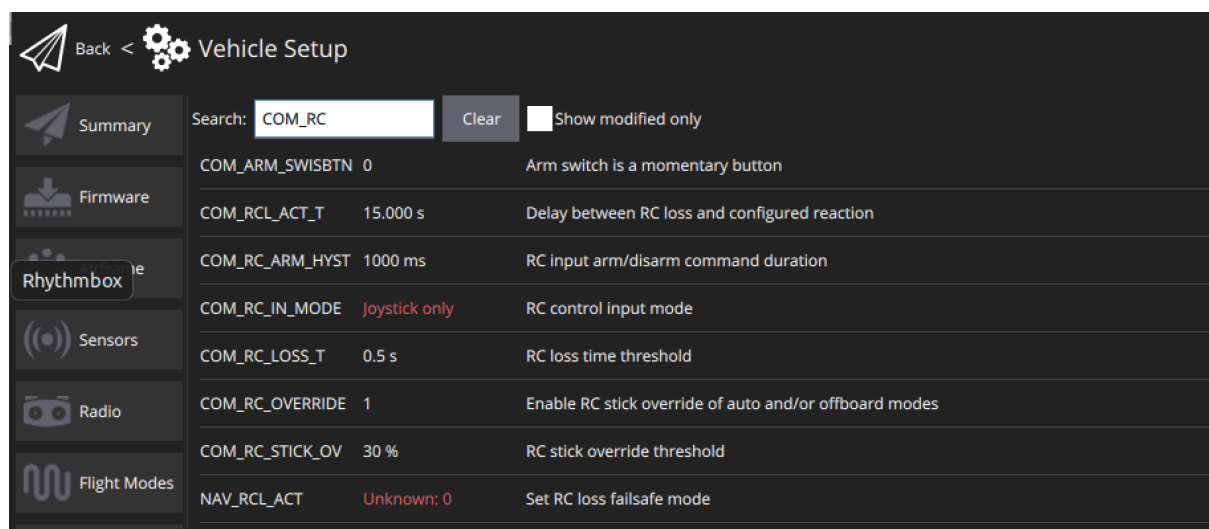


## Bootloader :

<https://nxp.gitbook.io/hovergames/downloads#rddrone-fmuk66-e-px4-bootloader>


## Configuration de la voiture :


- Désactiver la sécurité qui empêche de ARM le véhicule :  
<https://docs.px4.io/main/en/config/safety.html>
- Explication du code :  
<https://nxp.gitbook.io/nxp-cup/dfrobot-chassis-developer-guide-2019/development-to-ols/rddrone-fmuk66-development/the-example-application>
- Explications des différents paramètres à mettre sur QGroundControl  
[https://docs.px4.io/main/en/advanced\\_config/parameter\\_reference.html](https://docs.px4.io/main/en/advanced_config/parameter_reference.html)





- Paramètres de la PWM présents sur le site ci-dessous :


<https://nxp.gitbook.io/nxp-cup/mr-buggy3-developer-guide-2022/mr-buggy3-software-setup>


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FD_EXT_ATS_EN	0	Enable PWM input on for engaging failsafe from an external automatic trigger system (ATS)
FD_EXT_ATS_TRIG	1900 us	The PWM threshold from external automatic trigger system for engaging failsafe
MOT_SLEW_MAX	0.000 s/(1000*PWM)	Minimum motor rise time (slew rate limit)
PWM_MAIN_DIS1	-1	
PWM_MAIN_DIS2	1500	
PWM_MAIN_DIS3	-1	
PWM_MAIN_DIS4	1500	
PWM_MAIN_DIS5	-1	
PWM_MAIN_DIS6	-1	
PWM_MAIN_DISARM	1500	
PWM_MAIN_FAIL1	-1	
PWM_MAIN_FAIL2	-1	
PWM_MAIN_FAIL3	-1	
PWM_MAIN_FAIL4	-1	
PWM_MAIN_FAIL5	-1	
PWM_MAIN_FAIL6	-1	


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
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PWM_MAIN_FAIL6	-1
PWM_MAIN_MAX	2000
PWM_MAIN_MAX1	-1
PWM_MAIN_MAX2	1700
PWM_MAIN_MAX3	-1
PWM_MAIN_MAX4	2000
PWM_MAIN_MAX5	-1
PWM_MAIN_MAX6	-1
PWM_MAIN_MIN	1300
PWM_MAIN_MIN1	-1
PWM_MAIN_MIN2	1300
PWM_MAIN_MIN3	-1
PWM_MAIN_MIN4	1000
PWM_MAIN_MIN5	-1
PWM_MAIN_MIN6	-1
PWM_MAIN_RATE	400

## Configuration de la caméra :

- suivre les instructions de 1 à 4 dans <https://github.com/NXPHoverGames/PixyCam>

## PixyCam

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This is a Pixy2 driver for usage with PX4 Firmware (<https://github.com/PX4/Firmware.git>).

This driver includes I2C and SPI interfaces.

In the pixycam.cpp file is an example shown based on I2C communication. But the driver also can support SPI communication. The PixyCam repo is written to use with the [PX4 Firmware](#). You should be familiar with [PX4 Firmware](#) and [QGroundControl](#).

To use the driver and run the example, please follow the next steps:

1. Download or clone the PX4 Firmware: <https://github.com/PX4/Firmware.git>
2. Navigate to the following folder: ~/src/examples
3. Copy or clone this repo into this folder
4. Open the file ~/boards/nxp/fmuk66-v3/default.cmake and go to EXAMPLES (end of file). Add "PixyCam" in the last row (without the quotation marks) and save the file

- Configuration de caméra

[https://docs.pixycam.com/wiki/doku.php?id=wiki:v2:porting\\_guide](https://docs.pixycam.com/wiki/doku.php?id=wiki:v2:porting_guide)

- On utilise PixyMon en mettant ces configurations

