Pi + 飛控
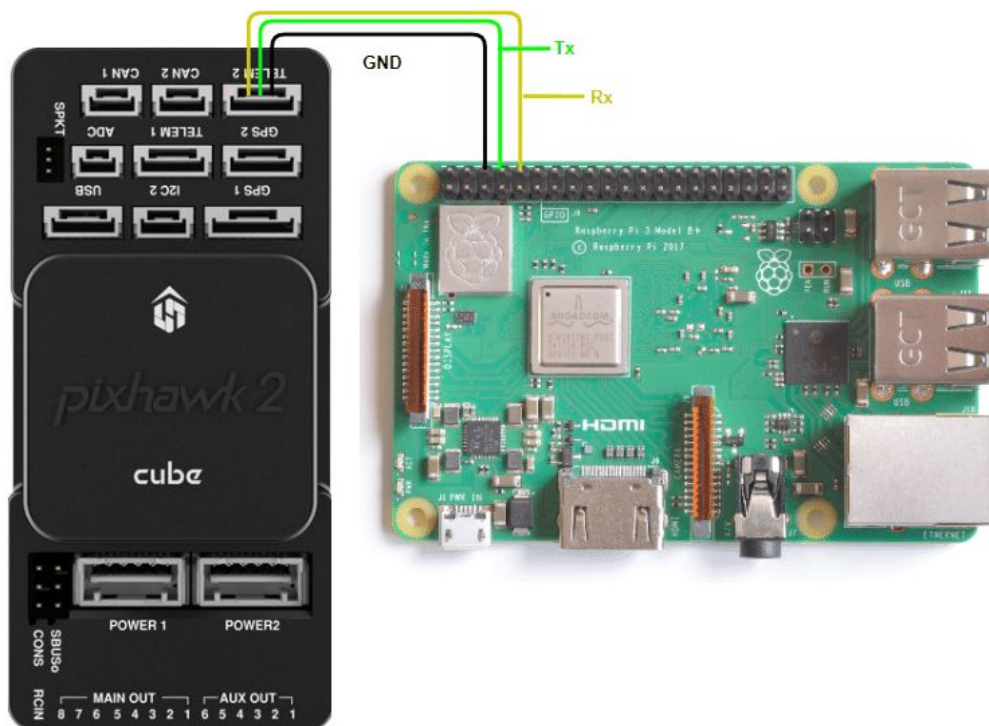
飛控版本 : cpoter V4.3.7 official
硬體架構 : here3+ (can)、cube+、Pi4B(telemetry to GPIO)
GPS設定參考 : GPS設定

- **硬體安裝**

將Telemetry接到Pi上的GPIO

MAVProxy安裝 :

```
sudo raspi-config
```

- **安裝MAVProxy**

```
sudo apt-get update && sudo apt-get upgrade -y
sudo apt-get install python3-pip
sudo apt-get install python3-dev
sudo pip3 install future
sudo apt-get install screen python3-wxgtk4.0 python3-lxml
sudo pip3 install pyserial
sudo pip3 install MAVProxy
```

關閉藍芽

```
sudo nano /boot/config.txt
```

在文件最下面加入

```
dtoverlay=disable-bt
```

重新開機

```
sudo reboot
```

執行mavproxy.py

```
sudo mavproxy.py --master=/dev/ttyACM0 --out=tcpin:0.0.0.0:14550
```

```
pi@raspberrypi: ~          ×   +  ⌄

pi@raspberrypi:~ $ sudo python3 mavproxy.py --master=/dev/serial0 --baudrate 57600
WARNING: You should uninstall ModemManager as it conflicts with APM and Pixhawk
Connect /dev/serial0 source_system=255
Log Directory:
Telemetry log: mav.tlog
Waiting for heartbeat from /dev/serial0
MAV> AP: ArduCopter V4.3.7 (c8506ed4)
AP: ChibiOS: a97ccb41
AP: CubeOrangePlus 0042003A 30325117 37363931
AP: RCOut: PWM:1-14
AP: IMU0: fast sampling enabled 2.0kHz
AP: IMU1: fast sampling enabled 9.0kHz/2.3kHz
AP: IMU2: fast sampling enabled 9.0kHz/2.3kHz
AP: Frame: QUAD/X
Detected vehicle 1:1 on link 0
online system 1
STABILIZE> Mode STABILIZE
Detected vehicle 1:0 on link 0
AP: ArduCopter V4.3.7 (c8506ed4)
AP: ChibiOS: a97ccb41
AP: CubeOrangePlus 0042003A 30325117 37363931
AP: RCOut: PWM:1-14
AP: IMU0: fast sampling enabled 2.0kHz
AP: IMU1: fast sampling enabled 9.0kHz/2.3kHz
AP: IMU2: fast sampling enabled 9.0kHz/2.3kHz
AP: Frame: QUAD/X
AP: ArduCopter V4.3.7 (c8506ed4)
AP: ChibiOS: a97ccb41
AP: CubeOrangePlus 0042003A 30325117 37363931
AP: RCOut: PWM:1-14
AP: IMU0: fast sampling enabled 2.0kHz
AP: IMU1: fast sampling enabled 9.0kHz/2.3kHz
AP: IMU2: fast sampling enabled 9.0kHz/2.3kHz
AP: Frame: QUAD/X
AP: PreArm: Throttle below failsafe
AP: PreArm: 3D Accel calibration needed
AP: PreArm: Compass not calibrated
Received 985 parameters (ftp)
Saved 985 parameters to mav.parm
MAV> fence present

STABILIZE> |
```