Console

MAVProxy Vehicle Link Mission Rally Fence Parameter

GUIDED ARM GPS: OK3 (10) Vcc 5.00 Radio: -- INS MAG AS RNG AHRS EKF LOG
Batt: 88%/12.19V 29.9A Link 1 OK 100.0% (5515 pkts, 0 lost, 0.00s delay)
Hdg 104/105 Alt 15m AGL ---/--- AirSpeed 8m/s GPSSpeed 8m/s Thr 48 Roll 0 Pitch -29 Wind
WP 0 Distance 279m Bearing 104 AltError 0m(L) AspdError 0m/s(H) FlightTime 0:52 ETR 0:00 Par

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G_off: 0.00, 0.00, 0.00

A_off: 0.00, 0.00, 0.00

A_scale: 1.00, 1.00, 1.00

Mode GUIDED
APM: Initialising APM...
Got MAVLink msg: COMMAND_ACK {command : 400, result : 0}
ARMED
Arming checks disabled
Got MAVLink msg: COMMAND_ACK {command : 22, result : 0}
Got MAVLink msg: COMMAND_ACK {command : 178, result : 0}
Got MAVLink msg: MISSION_ACK {target_system : 255, target_component : 0, type : 0, mission_type : 0}
height 15
Got MAVLink msg: MISSION_ACK {target_system : 255, target_component : 0, type : 0, mission_type : 0}
Got MAVLink msg: COMMAND_ACK {command : 178, result : 0}
Flight battery 90 percent

Map

View

Click: -35.36222303 149.16628430 (-35°21'44.00" 149°09'58.62") (S 55 696817 6084632) Distance: 127.286m 0.069nm Bearing 35.3

python3 simple_goto.py --connect udpin:127.0.0.1:14550

dronekit-sitl copter 75x32

```
fabiano@fabiano-B360M-AORUS-Gaming-3  ~  dronekit-sitl copter
os: linux, apm: copter, release: stable
SITL already Downloaded and Extracted.
Ready to boot.
Execute: /home/fabiano/.dronekit/sitl/copter-3.3/apm --home=-35.363261,149.
165230,584,353 --model=quad -I 0
SITL-0> Started model quad at -35.363261,149.165230,584,353 at speed 1.0
SITL-0.stderr> bind port 5760 for 0
Starting sketch 'ArduCopter'
Serial port 0 on TCP port 5760
Starting SITL input
Waiting for connection ....
bind port 5762 for 2
Serial port 2 on TCP port 5762
bind port 5763 for 3
Serial port 3 on TCP port 5763
```

mavproxy.py --master tcp:127.0.0.1:5760 --sitl 127.0.0.1:5501 --out --out 100x32

```
fabiano@fabiano-B360M-AORUS-Gaming-3  ~  mavproxy.py --master tcp:127.0.0.1:5760 --sitl 127.0.0
.1:5501 --out 127.0.0.1:14550 --out 127.0.0.1:14551 --map --console
Connect tcp:127.0.0.1:5760 source_system=255
Loaded module console
Loaded module map
Log Directory:
Telemetry log: mav.tlog
Waiting for heartbeat from tcp:127.0.0.1:5760
MAV> STABILIZE> Received 526 parameters
Saved 526 parameters to mav.parm
```

python3 simple_goto.py --connect udpin:127.0.0.1:14550 92x32

```
er  python3 simple_goto.py --connect udpin:127.0.0.1:14550  tcc

Connecting to vehicle on: udpin:127.0.0.1:14550
CRITICAL:autopilot:APM:Copter V3.3 (d6053245)
CRITICAL:autopilot:Frame: QUAD
Basic pre-arm checks
 Waiting for vehicle to initialise...
Arming motors
 Waiting for arming...
 Waiting for arming...
 Waiting for arming...
 Waiting for arming...
ERROR:autopilot:ARMING MOTORS
CRITICAL:autopilot:GROUND START
 Waiting for arming...
WARNING:dronekit:Link timeout, no heartbeat in last 5 seconds
CRITICAL:autopilot:Initialising APM...
Taking off!
 Altitude:  0.0
 Altitude:  0.01
 Altitude:  0.12
 Altitude:  1.65
 Altitude:  3.53
 Altitude:  5.62
 Altitude:  7.71
 Altitude:  9.16
 Altitude:  9.69
Reached target altitude
Set default/target airspeed to 3
Going towards first point for 30 seconds ...
Going towards second point for 30 seconds (groundspeed set to 10 m/s) ...
```