

The background of the slide features abstract, overlapping geometric shapes in various shades of blue and a bright yellow. These shapes create a dynamic, modern feel, with some elements resembling stylized waves or swooshes. The central area of the slide is white, providing a clean space for the title and footer text.

Application of TF-Luna in Pixhawk

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TF-Luna can directly be connected with the serial port of Pixhawk. TF-Luna can be used in flight device for the purpose of altitude holding or obstacle avoidance. This document is suitable to Pixhawk adopts ArduCopter V4.0.0 or higher firmware.

Example for connecting Pixhawk:

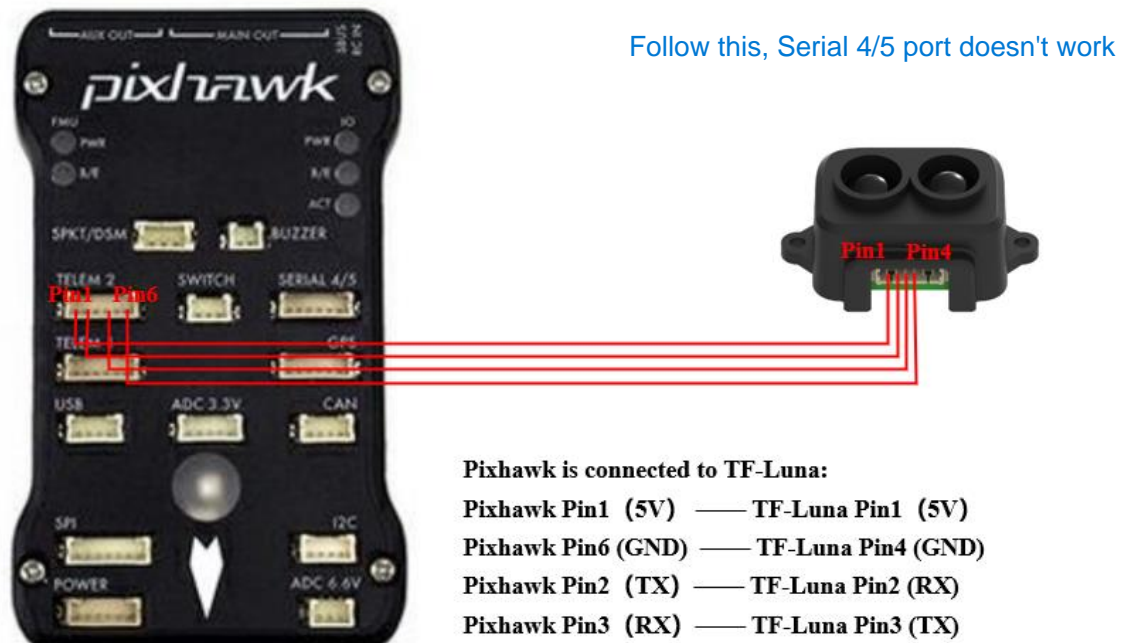


Figure 1 Schematic Diagram of Connecting TF-Luna with TELEM 2 Interface (Serial Port 2) of Pixhawk

a) Mission Planner configuration description of TF-Luna for the purpose of altitude hold

Connect the flight control board to MP. **Attention: the installation height should be bigger than non-detection zone.** Select [Full Parameter List] in the left from the below bar- [CONFIG/TUNING] . Find and modify the following parameters:

SERIAL2_PROTOCOL = 9 [Rangefinder option]

SERIAL2_BAUD = 115 [Choose the current LiDAR baud rate, if haven't been changed, the default baud rate 115200 should be selected, that is 115]

RNGFND_TYPE = 20 [Same option with TFmini]

RNGFND_MIN_CM = 20 [It could be changed according to real demands and should be bigger LiDAR than non-detection zone, unit is cm]

RNGFND_MAX_CM = 200 [It could be changed according to real demands but should be smaller than effective measure range of LiDAR, unit is cm]

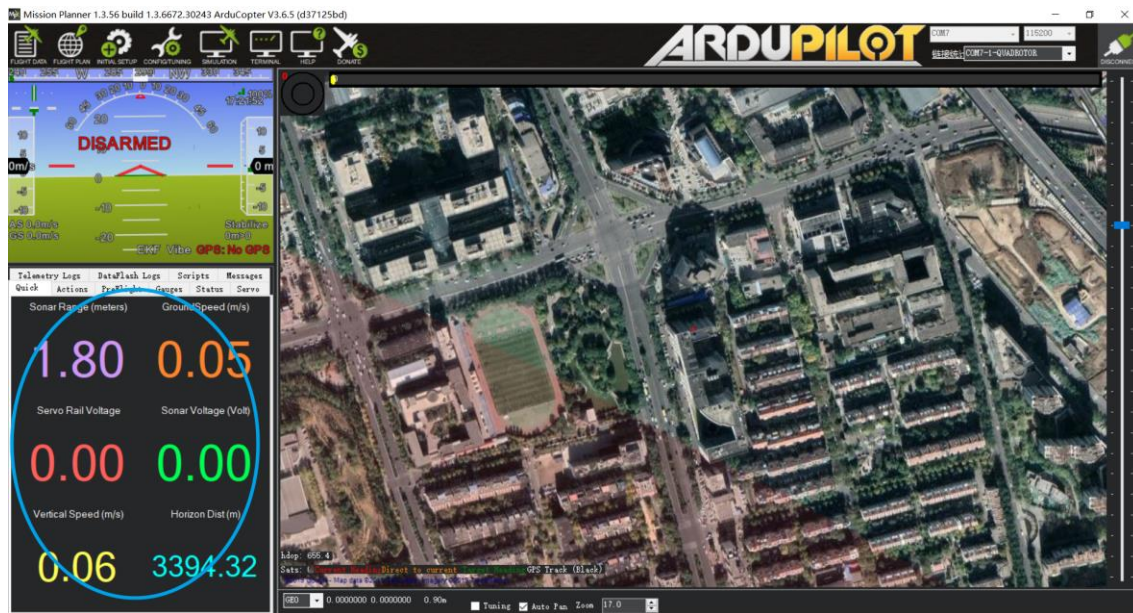
RNGFND_GNDCLEAR = 15 [expressed in cm, depending upon mounting height of the module and should be bigger LiDAR than non-detection zone]

PE=0

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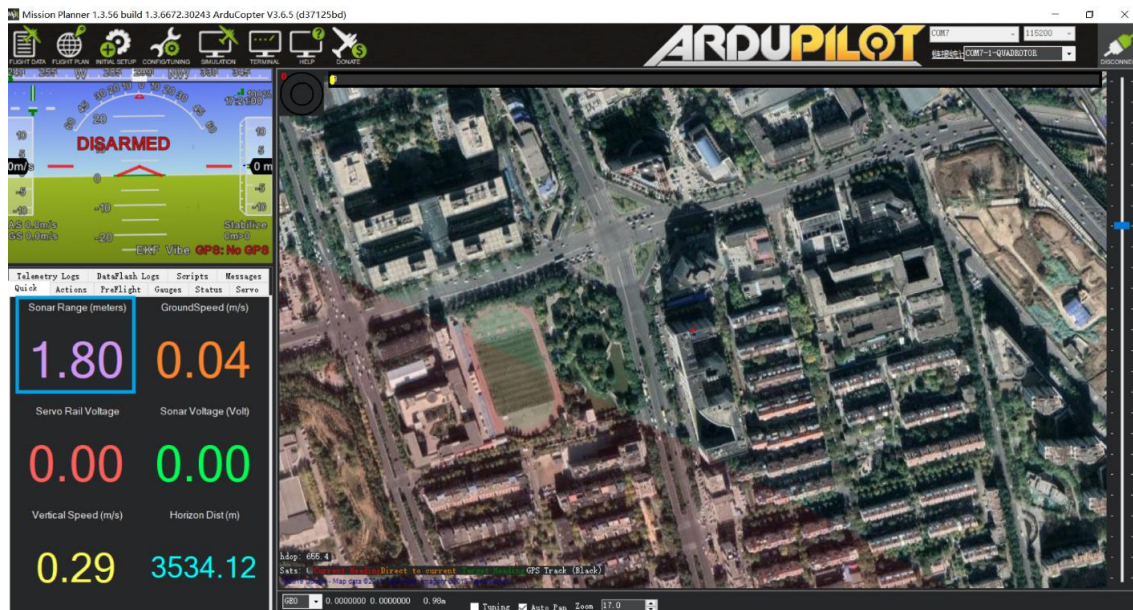
or message “I

see the altitude

tion *sonarran*

The altitude distance from the LiDAR will be displayed in Sonar Range(meters),see the following picture:

b) Mission Planner configuration description of TF-Luna for the purpose of Obstacle Avoidance



It's only recommended to be used in Loiter mode, the detail setting is as followings:

Connect the flight control board to MP. **Attention:distance between UAV margin and LiDAR should be bigger than LiDAR non-detection zone.** Select [Full Parameter List] in the left from the below bar-[CONFIG/TUNING] . Find and modify the following parameters:

AVOID_MARGIN=3 [Unit: m, set obstacle avoidance distance as required]

SERIAL2_PROTOCOL = 9 [Rangefinder option]

SERIAL2_BAUD = 115 [Choose the current LiDAR baud rate,if haven't been changed,the default baud rate 115200 should be selected,that is 115]

RNGFND_TYPE = 20 [Same option with TFmini]

RNGFND_MIN_CM = 20 [It could be changed according to real demands and should be bigger LiDAR than non-detection zone,unit is cm]

RNGFND_MAX_CM = 200 [It could be changed according to real demands but should be smaller than effective measure range of LiDAR,unit is cm]

RNGFND_GNDCLEAR = 15 [Unit: cm, depending upon mounting height of the module and should be bigger LiDAR than non-detection zone]

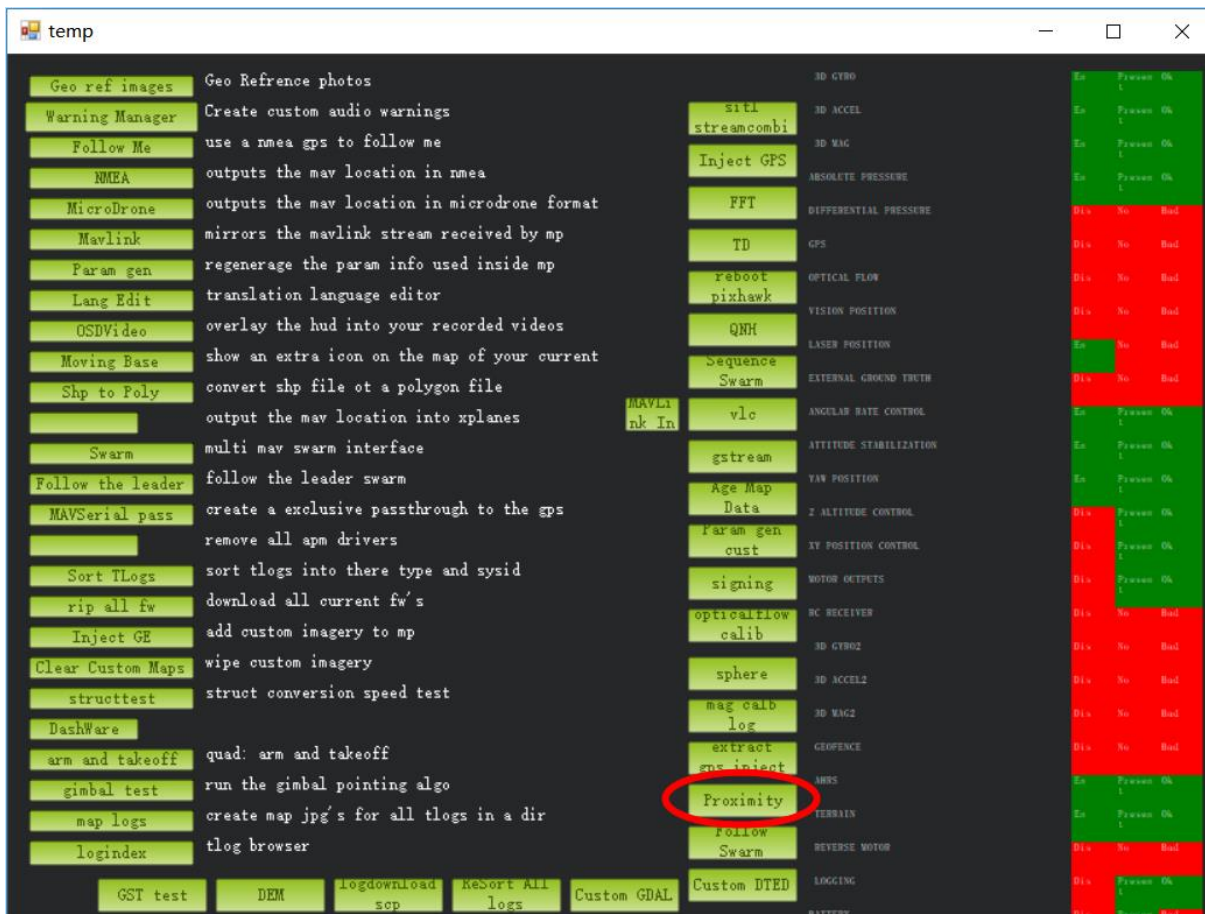
RNGFND_ORIENT=0 [It depends on the LiDAR's real installation direction,0~7 is supported up to now,see detail in MP]

PRX_TYPE=4 [RangeFinder should be selected for proximity sensor in obstacle avoidance mode]

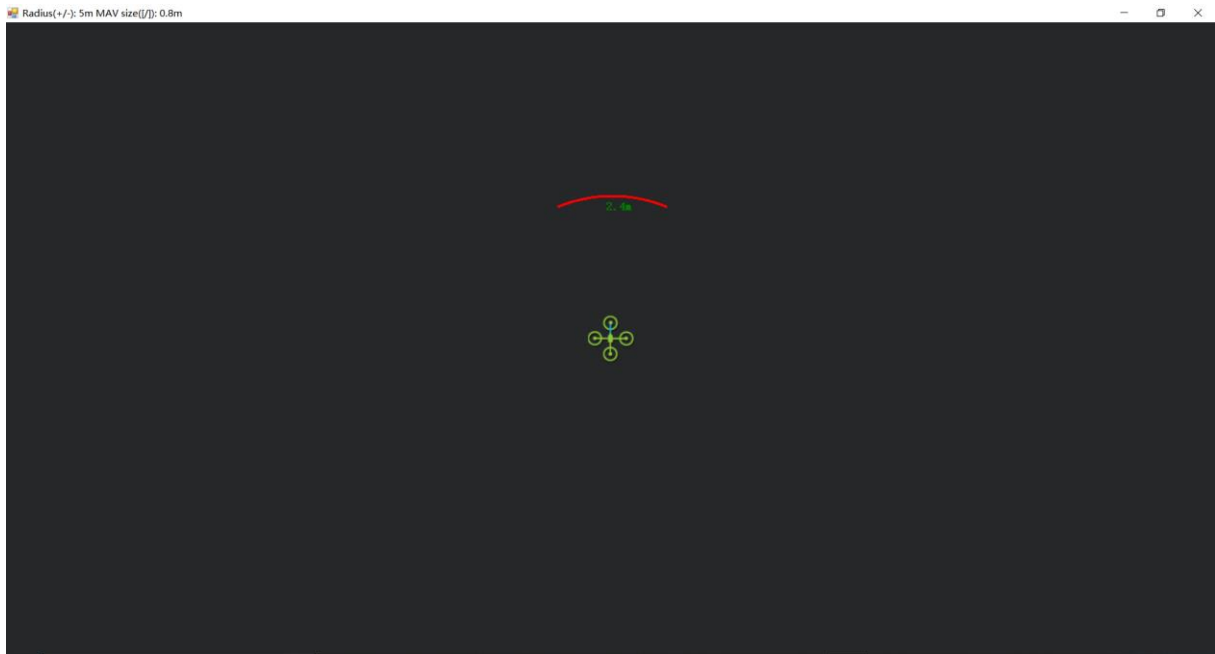
Upon setting of these parameters, click [Write Params] on the right of the software to finish.

If the error message “**Bad Lidar Health**” appears, please check if the connection is correct and the power supply is normal, then restart Pixhawk.

How to see the target distance from the LiDAR:(distance from LiDAR in obstacle avoidance can't be displayed in *sonarrange* option)press *Ctrl+F* button in keyboard,the following window will pop out:



Click button *Proximity*,the following window will appear:



The number in green color means the distance from LiDAR in obstacle avoidance mode (the number only refresh when this window open,close,zoom in or zoom out,it doesn't mean the real time distance from LiDAR and will not be influenced in Mission Planner version under v1.3.48,the problem could be solved by updating Mission Planner)

- ✧ **Attach:** If TELEM 2 port has been used, SERIAL4/5 interface could be used, the other settings are same

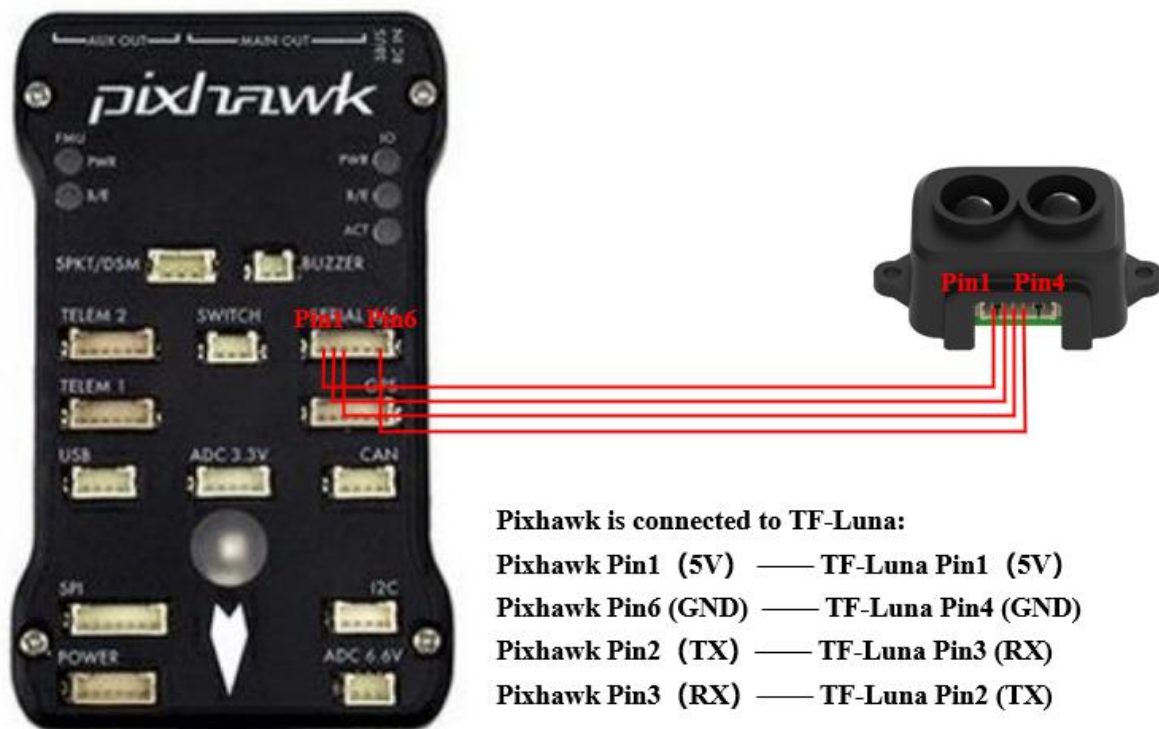


Figure 2 Schematic Diagram of Connecting TF-Luna with SERIAL4/5 Interface (Serial Port 4/5) of Pixhawk

Configuration Descriptions of Mission Planner

Connect flight control board to MP, Select [Full Parameter List] in the left from the below bar [CONFIG/TUNING]. Find and modify following parameters:

SERIAL4_PROTOCOL = 9 (LiDAR)

SERIAL4_BAUD = 115

Upon setting of these parameters, the other parameters should be same as Mission Planner configuration description of TF-Luna for the purpose of Obstacle Avoidance or Altitude Holding, then click [Write Params] on the right of the software to finish.