

Connection

COM20 Disconnect

Board: version 3.0      Firmware: 2.42 b7

Profile

Profile2 Rename

Load... Save...

[basecamelectronics.com](http://basecamelectronics.com)

PID Controller

	P	I	D
ROLL	22	0.15	25
PITCH	22	0.15	25
YAW	8	0	10

AUTO

Motor Configuration

	POWER	+	INVERT	NUM.POLES
ROLL	150	0	<input type="checkbox"/>	14
PITCH	150	0	<input type="checkbox"/>	14
YAW	150	30	<input checked="" type="checkbox"/>	22

AUTO

Adaptive PID gains control

ROLL     PITCH     YAW

RMS error threshold: 10

Attenuation rate: 50

Recovery factor: 6

Sensor

Axis TOP: -Z    RIGHT: X

Skip Gyro calibration at startup

CALIB.ACC    CALIB.GYRO

Configure: Camera IMU    Frame IMU

MOTORS ON/OFF    READ    WRITE

Cycle time: 801    I2C errors: 48



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**AHRS**

Gyro trust: 100

Accelerations compensation

**Timings**

Serial port speed: 115200

PWM frequency: LOW (noisy)

**Motor outputs**

ROLL: ROLL out

PITCH: PITCH out

YAW: YAW out

**External FC Gain**

ROLL: 0

PITCH: 0

AUTO

**Sensor**

Gyro LPF: 0

Gyro high sensitivity

I2C pullups enable

Frame IMU: Below YAW

**Misc.settings**

Log real-time data to file

Rewrite on reconnection

MOTORS ON/OFF READ WRITE

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- Basic
- Advanced
- RC**
- Service
- Follow
- Monitoring
- Upgrade
- Filters

**Input Mapping**

RC\_ROLL pin mode: Normal (PWM or Analog)

ROLL: no input

PITCH: RC\_PITCH - PWM

YAW: RC\_YAW - PWM

CMD: no input

FC\_ROLL: no input

FC\_PITCH: no input

**Command Assignment**

LOW: no action

MID: no action

HIGH: no action

**Mix channels**

FC\_ROLL: none 0%

FC\_PITCH: none 0%

**RC Control**

	ANGLE	SPEED	INVERSE	MIN.ANGLE	MAX.ANGLE	SPEED	LPF	INIT.ANGLE
ROLL	<input type="radio"/>	<input checked="" type="radio"/>	<input type="checkbox"/>	0	0	0	3	0
PITCH	<input checked="" type="radio"/>	<input type="radio"/>	<input type="checkbox"/>	0	80	20	3	0
YAW	<input type="radio"/>	<input checked="" type="radio"/>	<input type="checkbox"/>	-180	180	3	5	0

MOTORS ON/OFF      READ      WRITE

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**Menu Button**

Assign actions to menu button:

1 click: Calibrate ACC

2 clicks: Calibrate Gyro

3 clicks: Use profile Profile3

4 clicks: no action

5 clicks: Swap RC PITCH<->ROLL

Long press: no action

Remember last used profile

**Battery Monitoring**

**11.40 V** Calibrate

Low voltage - alarm  
Threshold, V: 10.8

Low voltage - stop motors  
Threshold, V: 9.9

Compensate voltage drop  
Full battery, V: 12.6

Set defaults for: 3s LiPo

**Buzzer**

Command confirmation       Alarms       Beep with motors

Calibration       Errors

MOTORS ON/OFF

READ

WRITE

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Connection

COM20 [dropdown] Disconnect [button]

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Profile

Profile2 [dropdown] Rename [button]

Load... [button] Save... [button]

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Disabled

Estimate frame angles from motors

Follow Flight Controller, %

ROLL [0] [spin]

PITCH [0] [spin]

Follow PITCH,ROLL

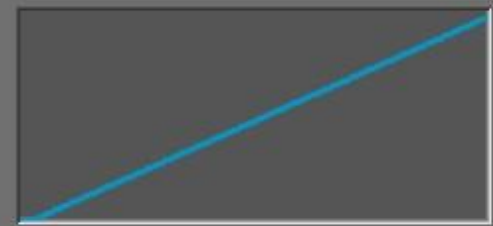
Follow ROLL start, deg [40] [spin]

Follow ROLL mix, deg [20] [spin]

Follow YAW

Deadband in degrees: [10] [spin]

Expo curve: [0] [spin]



	OFFSET	SPEED	LPF
ROLL	[20] [spin]	[10] [spin]	[3] [spin]
PITCH	[56] [spin]	[10] [spin]	[3] [spin]
YAW	[0] [spin]	[10] [spin]	[3] [spin]

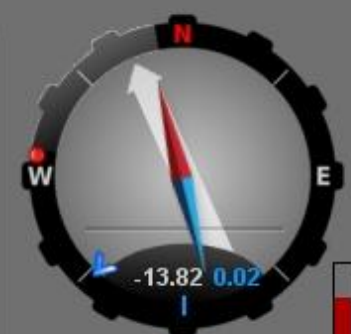
[AUTO] [button]

MOTORS ON/OFF [button]

READ [button]

WRITE [button]

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Frame rate: 20 PAUSE

Receive extended debug info

- RC\_ROLL
- RC\_PITCH
- RC\_YAW
- RC\_CMD
- EXT\_FC\_ROLL
- EXT\_FC\_PITCH

- ACC\_X -3
- ACC\_Y -1
- ACC\_Z 510
- GYRO\_X 2
- GYRO\_Y 0
- GYRO\_Z -1
- ERR\_ROLL -2
- ERR\_PITCH -4
- ERR\_YAW -558
- POWER\_ROLL 150

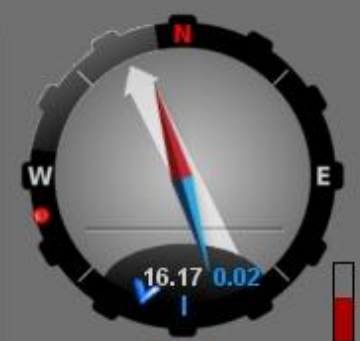


MOTORS ON/OFF

READ

WRITE

Cycle time: 801    I2C errors: 93



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Automatic   Manual

Device SN: 012314b5a4af952dee READ

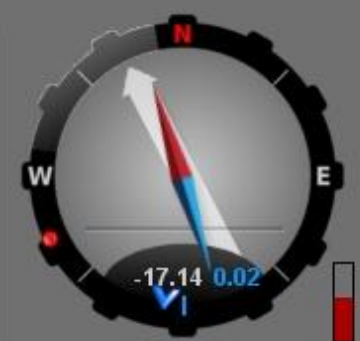
Current version: 2.42 b7

Latest version: - CHECK  Check at startup

Upgrade to version: UPGRADE!

MOTORS ON/OFF READ WRITE

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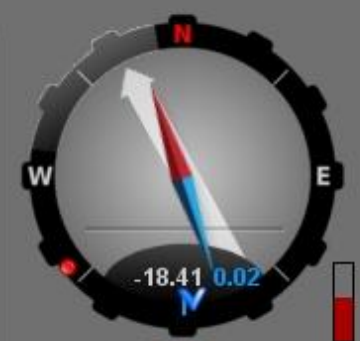
[basecamelectronics.com](http://basecamelectronics.com)

Notch filters

	Frequency, Hz	Width, Hz	Enabled
ROLL	0	0	<input type="checkbox"/>
	0	0	<input type="checkbox"/>
	0	0	<input type="checkbox"/>
PITCH	0	0	<input type="checkbox"/>
	0	0	<input type="checkbox"/>
	0	0	<input type="checkbox"/>
YAW	0	0	<input type="checkbox"/>
	0	0	<input type="checkbox"/>
	0	0	<input type="checkbox"/>

Low-pass 2nd order

	Frequency, Hz	Enabled
ROLL	0	<input type="checkbox"/>
PITCH	0	<input type="checkbox"/>
YAW	0	<input type="checkbox"/>



MOTORS ON/OFF

READ

WRITE

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