

1. Power supply and trigger signal

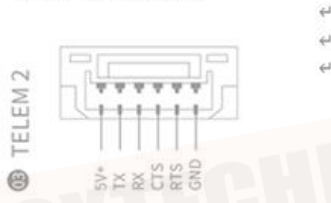


2. Flight Controller Setting (take CUAV V5+ as an example)

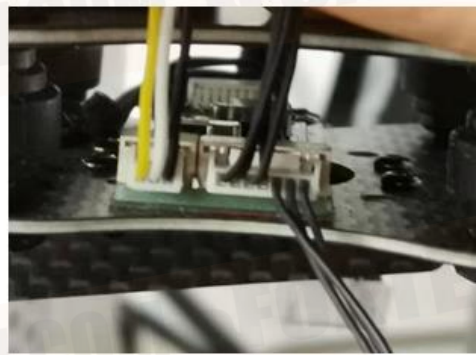
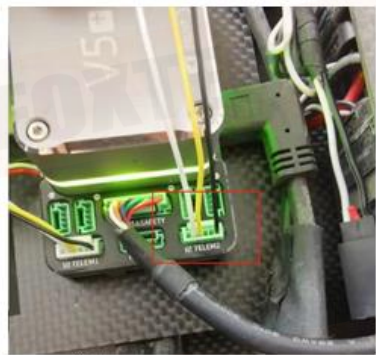
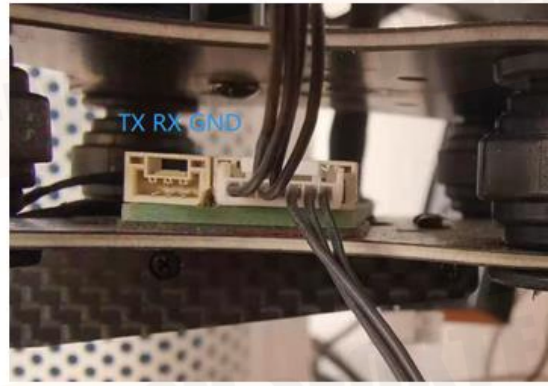
CAM_TRIGG_TYPE	1	RELAY Trigger
RELAY_PIN	54	aux5 Trigger
BRD_PWM_COUNT	2	AUX1 AUX2 : pwm output, others-relay
servo13_function	10	camera trigger
CAM_RELAY_ON	0	low level trigger

3. Gimbal Control Wiring (take CUAV V5+ as an example)

用 GH1.25 6pin 对 3pin 连接线连接飞控和云台 (以下以 CUAV V5+ 为例)。连接飞控的 TELEM2 和云台的串口; ←



connect flight controller and gimbal with GH1 25 6pin and 3pin wires. Connect FC TELEM2 port to gimbal serial ports.



4. Gimbal Control Setting

(1) Set the value of TELEM2 , search for TELEM2 in "all parameters table" of MP configuration/ debugging, and modify as the following figure:

命令	值	单位	选项	描述	Fav
SERIAL2_BAUD	115		1:1200 2:2400 4:4800 9:9600 19:19200 38:38400 57:57600 111:111100 115:115200 256:256000 500:500000 921:921600 1500:1500000	The baud rate of the Telem2 port. Most stm32-based boards can support rates of up to 1500. If you setup a rate you cannot support and then can't connect to your board you should load a firmware from a different vehicle type. That will reset all your parameters to defaults.	
SERIAL2_PROTOCOL	7		-1:None 1:MAVLink1 2:MAVLink2 3:Frsky D 4:Frsky SPort 5:GPS 7:Alexmos Gimbal Serial 8:S ToRM32 Gimbal Serial 9:Rangefinder 10:FrSky SPort Passthrough (Open TX) 11:Lidar360 13:Beacon 14:Volz servo out 15:SBUS servo out 16:ESC Telemetry 17:Devo Telemetry 18:OpticalFlow 19:RobotisServo 20:NMEA Output 21:WindVane 22:SLCAN 23:RCIN	Control what protocol to use on the Telem2 port. Note that the Frsky options require external converter hardware. See the wiki for details.	

加载

保存

写入参数

刷新参数

比较参数

所有单位都会以原始格式储存, 不会被编

3DR_Trisk_AC34

加载参数

重置为默认值

搜索

TELEM2

Modified

(2) Set in the initial settings of MP - optional hardware - camera/gimbal, the settings are as follows:

Mission Planner 1.3.74 build 1.3.7563.27684 ArduCopter V4.0.6 (13b6478d)

安装固件

>> 必要硬件

>> 可选硬件

RTK/GPS Inject

SiK电台(数传)

电池监测器

电池监测器2

UAVCAN

Joystick

指南针/电机 校准

声响

空速

PX4Flow 光流

光流

OSD

相机云台

电机测试

蓝牙设置

降落伞

ESP8266 设置

Antenna Tracker

Type: Alexmos Serial

Tilt: Disable

Roll: Disable

Pan: [Dropdown]

快门: Relay

舵机限位: 最小 1000, 最大 2000

角度限位: 最小 -45, 最大 45

输入通道: RC6

控制角度: X 180, Y 180, Z 180

快门: 未按下 1300, 持续时间 1100, 10

请设置通道7为相机触发器

对应需要设置控制云台角度的遥控器通道, 建议用三档开关控制三个角度

the remote control channel needs to be set to control the angle of the gimbal, it is recommended to use the three-position switch to control the three angles.

Note: After setting, you need to restart the flight controller to take effect.