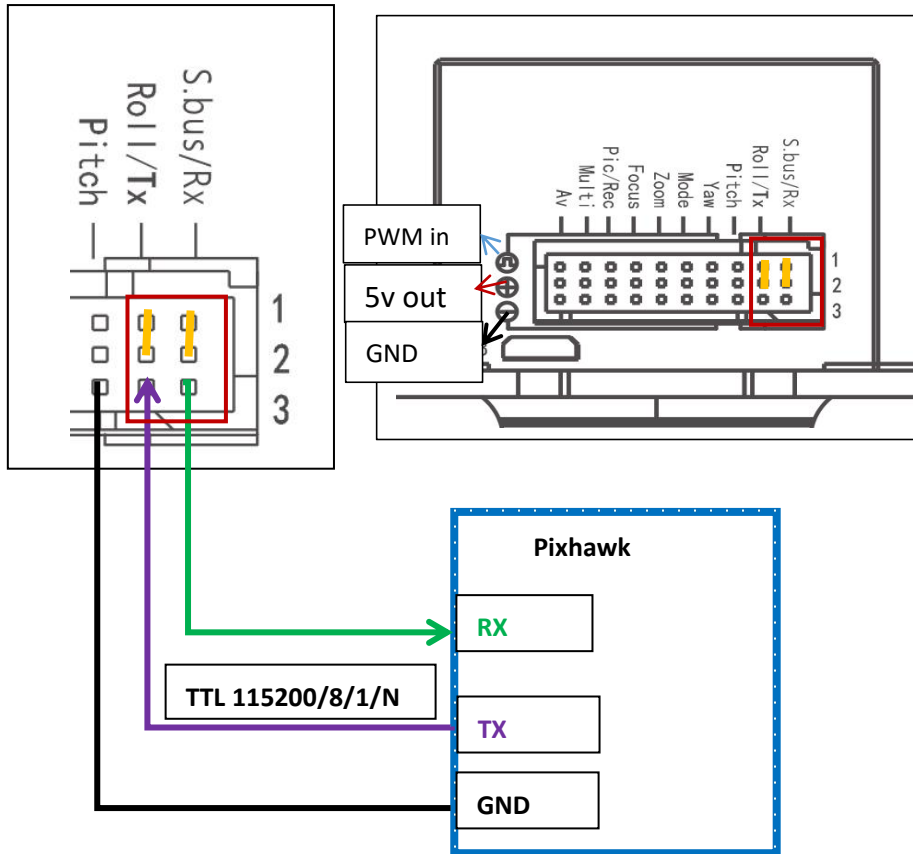


How to connect gimbal to pixhawk with serial port ?

Step 1: Serial port of gimbal connect to Pixhawk serial port (telem1 or telem2)



Step2 : Set pixhawk baudrate to 115200 and protocol select mavlink1. (eg, use mission planner)

Mp Mission Planner 1.3.62 build 1.3.6917.15581 ArduCopter V3.6.4 (6c4da9e3)



飞行模式
地理围栏
基本调参
扩展调参
标准参数
高级参数
全部参数表
全部参数树
Planner

写入参数 刷新参数 查找

Telem1 Baud Rate (SERIAL1_BAUD)
描述: The baud rate used on the Telem1 port. The APM2 can support all baudrates up to 115, and also can support 500. The PX4 can support rates of up to 1500. If you setup a rate you cannot support on APM2 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.

115200

Telem1 protocol selection (SERIAL1_PROTOCOL)
描述: Control what protocol to use on the Telem1 port. Note that the Frsky options require external converter hardware. See the wiki for details.

MAVLink1

Telemetry 2 Baud Rate (SERIAL2_BAUD)
描述: The baud rate of the Telem2 port. The APM2 can support rates of up to 115, and also can support 500. The PX4 can support rates of up to 1500. If you setup a rate you cannot support on APM2 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.

115200

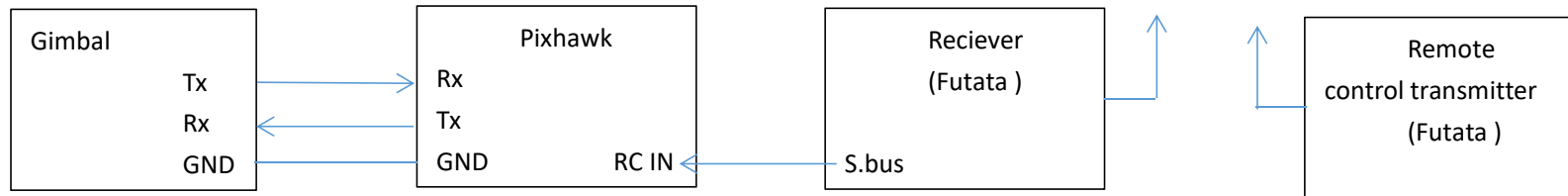
Telemetry 2 protocol selection (SERIAL2_PROTOCOL)
描述: Control what protocol to use on the Telem2 port. Note that the Frsky options require external converter hardware. See the wiki for details.

MAVLink1

Search For
Enter a single word to search for
TELEM
OK Cancel

6 just change the telem port connect to gimbal

Use “RC IN” connect to S.bus port of futaba reciever, user can control gimbal by futaba remote controller.



RC channels command set:

command_1: AA 55 10 01 FF (1~7ch)

YAW = chan_1; PITCH = chan_2; MODE = chan_3; ZOOM= chan_4; FOCUS=chan_5; PIC/REC = chan_6;

MULTI = chan_7

command_2: AA 55 10 02 FF 6~12ch

YAW = chan_6; PITCH = chan_7; MODE = chan_8; ZOOM= chan_9; FOCUS=chan_10; PIC/REC = chan_11; MULTI = chan_12

command_3: AA 55 10 03 FF 9~15ch

YAW = chan_9; PITCH = chan_10; MODE = chan_11; ZOOM= chan_12; FOCUS=chan_13; PIC/REC = chan_14; MULTI = chan_15

User can assign channels freely:

Step1: enter custom mode: AA 55 10 04 FF

Step2: AA 55 11 YA PI MO ZO FO PR MU FF (set no used channel to 0)

YA= yaw channel number value: 0x01~0x14

PI= pitch channel number value: 0x01---0x14

MO=mode channel number value: 0x01---0x14



ZO=ZOOM channel number value: 0x01---0x14

FO=FOCUS channel number (the function maybe changed by PN: PiP/IR color/laser control) value: 0x01---0x14

PR=PIC&REC channel number value: 0x01---0x14

MU=MULTI channel number value: 0x01---0x14

For example: use 9~15 note: all data is hex, **AA 55 11 09 0A 0B 0C 0D 0E 0F FF**

For example: use 7~13 chan to control gimbal: **AA 55 11 07 08 09 0A 0B 0C 0D FF**

Note: if you find time on OSD is not your local time:, use command to change the time zone :

command: AA 55 04 TZ FF TI = Time Zone

For example: the time zone of Beijing is 8, send AA 55 04 08 FF

Restart the gimbal after send command of time zone.