



Stabilize / AltHold / Loiter ☐

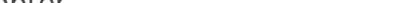
- [Follow Me ☐](#)
- [Guided ☐](#)
- [Acro ☐](#)
- [AirMode](#)
- [AltHold ☐](#)
- [Auto ☐](#)
- [Brake ☐](#)
- [Circle ☐](#)
- [SystemID ☐](#)
- [Drift ☐](#)
- [☐](#)
- [Flip ☐](#)
- [FlowHold ☐](#)
- [Follow ☐](#)
- [Land ☐](#)
- [Loiter ☐](#)
- [PosHold ☐](#)
- [RTL ☐](#)
- [Simple / Super Simple ☐](#)
- [SmartRTL ☐](#)
- [Sport ☐](#)
- [Stabilize ☐](#)
- [Throw ☐](#)
- [☐](#)
- [Turtle ☐](#)
- [ZigZag ☐](#)

Follow Me



GUIDED 84. APM OS X, MAVLink Windows Android DroidPlanner.



1.  Copter
2.  ( / )
3. GPS USB    .



1. `Loiter`
2. `Copter` `MAVLink`
3. Ensure
4. `Loiter` ()
5. `"` `"` `,`
6. `-F` `"` `"`

../images/followme1.jpg_

- ☐ ☐ ☐ ☐ ☐ ☐ ☐ ☐ ☐ ☐ ☐ GPS ☐ ☐ ☐ ☐ ☐ ☐ ☐ ☐ baud ☐ ☐ ☐

../images/followme2.png

- 如果“跟随”模式失败，则GPSI2C模块将返回Copter“跟随”模式失败
- 如果GPSI2C模块返回失败，则Copter将进入“跟随”模式失败
- 如果GPSI2C模块返回失败，则Copter将进入“跟随”模式失败
 - 如果GPSI2C模块返回失败，则Copter将进入“跟随”模式失败
 - 如果GPSI2C模块返回失败，则Copter将进入“跟随”模式失败

如果

如果GPSI2C模块返回失败，则Copter将进入“跟随”模式失败。如果GPSI2C模块返回失败，则Copter将进入“跟随”模式失败。如果GPSI2C模块返回失败，则Copter将进入“跟随”模式失败。


```

**Mission Planner **.

```

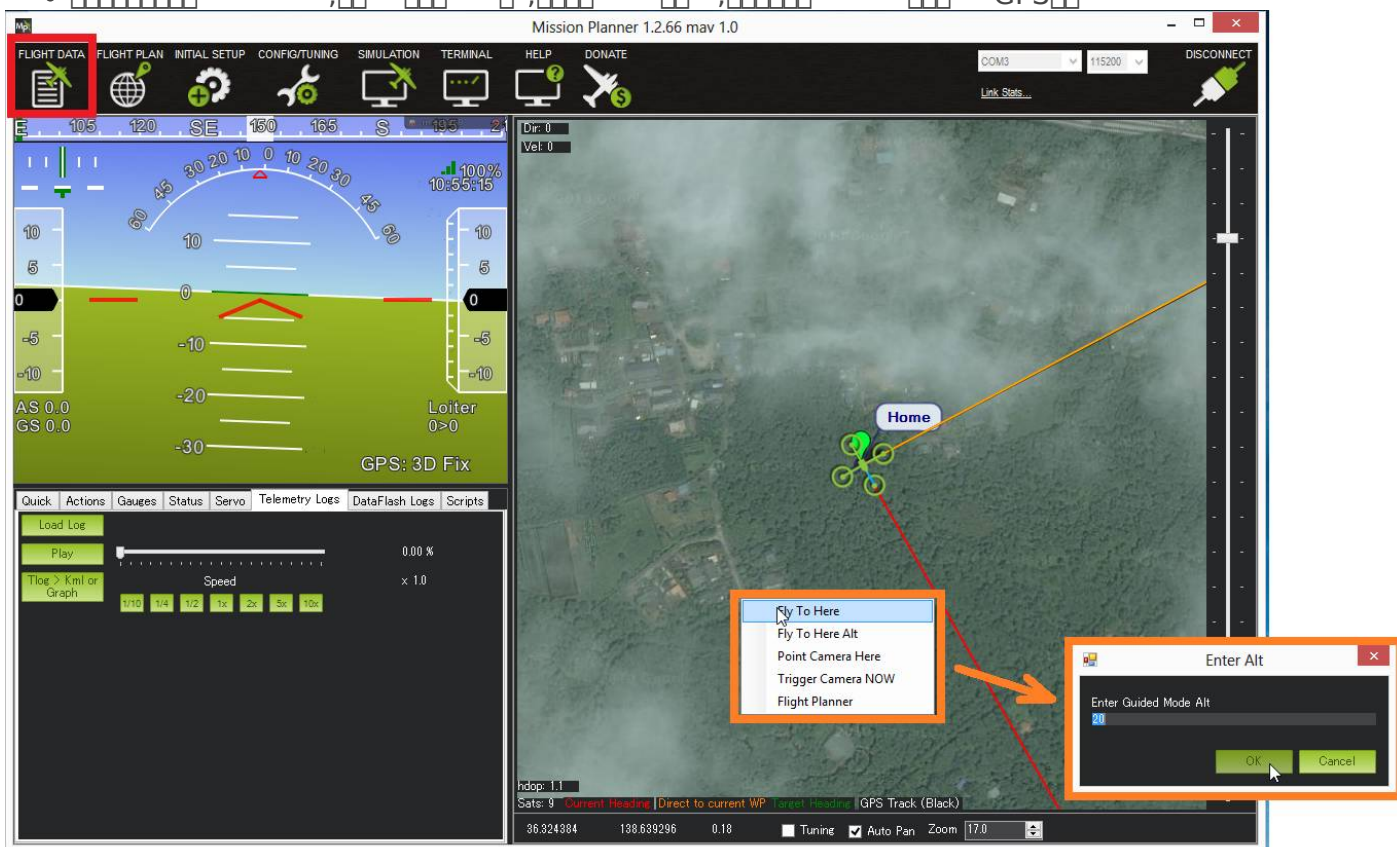
MAVLink  

● 

[illegible]

<table border="1"><tr><td></td><td></td></tr></table>			,	<table border="1"><tr><td></td><td></td><td></td><td></td><td></td><td></td></tr></table>						

GPS



- [illegible]



(**WP SPD**) Pids
 (). 10 10m/s 10m/ ? 13 /

                (WP SPD UP ()) (WP SPD DN (()).) WP
ACC Z                

[illegible][illegible]

項目	説明
0	XXXXXXXX
2	XXXX yaw XX
3	SetAttitudal XXXXXXXX
4	XXXX XY
5	XXXX XY
6	XXXXXXXXXX
7	XXXX

0(□ " 1") □□ RC □□□□□□□□□□

Bit 2 (□□ "4") □□□□□□ □□□□□□ RC □□□□□□□□

bit 3(“8”) () (2018-0 ()). SET ATITUDE TARGET MAVLINK
 : ,

4("16") XY .
 ,

Bit 5("32")

6("64") S-Curve (**)
 , . **
 ** **Bendy Ruler** ** **Dijkstras**

7 (" 128 ") **

/ ()
() () () 3 .

(NoGPS)

GPS GPS,
 AltHold .

guided NoGPS GPS(GPS) . ** GPS ,

Acro

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Acro [] RC [] , [] ()
[] Acro [] , [] , FPV [] **INS GYRO FILTER** ([]).
[], [], []
[] - [] []

The following are some examples of how you can set up your flight controller's configuration parameters:


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1 
AC 



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□□□□ □□□ l- ter 34. □□

00 “000”000 (bit 1 of) **AC** 00), 000000 I-term(integral term) 000000 P 000000 .
 00 I 000000000000 , 00 BetaFlight 000000 . 0 Betaflight 0000000000
 0 ArduPilot 00 (0), 000000000000 Betafly 000000 .

1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19	20	21	22	23	24	25	26	27	28	29	30	31	32	33	34	35	36	37	38	39	40	41	42	43	44	45	46	47	48	49	50	51	52	53	54	55	56	57	58	59	60	61	62	63	64	65	66	67	68	69	70	71	72	73	74	75	76	77	78	79	80	81	82	83	84	85	86	87	88	89	90	91	92	93	94	95	96	97	98	99	100
---	---	---	---	---	---	---	---	---	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	----	-----

- , PID .
- I-term(roll, pitch, yaw) P (. **ATC ANG RLL P** ().),
 , .
- , , .

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- 在 1990 年，IBM 公司推出了其第一代 Acro 系统，该系统采用 386 处理器，运行在 386 平台上，支持 386 指令集，并采用 386 总线。该系统采用 386 处理器，运行在 386 平台上，支持 386 指令集，并采用 386 总线。
- Copter 系统 Acro 系统，该系统采用 386 处理器，运行在 386 平台上，支持 386 指令集，并采用 386 总线。该系统采用 386 处理器，运行在 386 平台上，支持 386 指令集，并采用 386 总线。
- 该系统采用 386 处理器，运行在 386 平台上，支持 386 指令集，并采用 386 总线。该系统采用 386 处理器，运行在 386 平台上，支持 386 指令集，并采用 386 总线。



Acro[] [] [] [] [] [] [] [] [][] [] [] [] [] [] [] [] [] , [][] [][] Acro[] [] [] [] [] [] [] [] GPS,
 [] [] [] [] [] [] [] [] RTL[][] . [] [] [] [] [] [] [] [] [][] [][] [][] [][] [][]

<https://youtu.be/tC0mF-N5z0Q> date= ().

“  : 100%

□□□□ ACRO□□□□ * □□ **FPV□□□□□□

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Acro

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 .

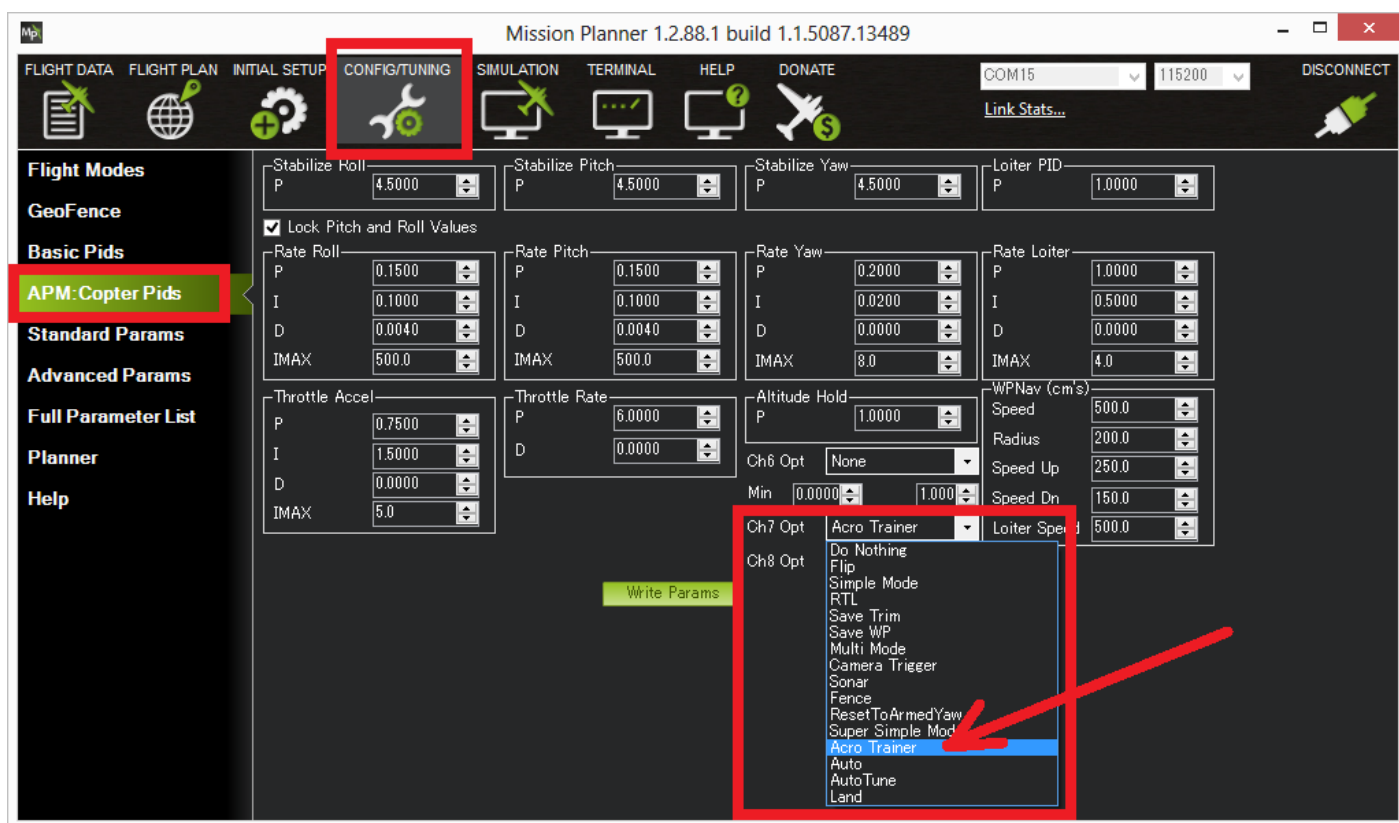
--	--

Acro

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****ACRO TRAINER **** :

- 0=  
- 1=  .   ,    **ACRO BAL**
ROLL() **ACRO BAL PITCH**   1.0   30deg/sec
  
- 2  () =    1, 
 45 ( **ATC ANGLE MAX** )



AirMode

ACRO STABILIZE 模式，在 ACRO STABILIZE 模式下，飞行器将保持水平姿态，并尝试保持高度。在 ACRO 模式下，飞行器将保持水平姿态，并尝试保持高度。



ACRO 模式下，飞行器将保持水平姿态，并尝试保持高度。在 ACRO 模式下，飞行器将保持水平姿态，并尝试保持高度。

ARM/DISARM Airmode(154) 模式下，飞行器将保持水平姿态，并尝试保持高度。

```
RCx 154 ARM/DISARM Airmode(154) 模式下，飞行器将保持水平姿态，并尝试保持高度。
```

AIRMODE 模式下，飞行器将保持水平姿态，并尝试保持高度。在 AIRMODE 模式下，飞行器将保持水平姿态，并尝试保持高度。

```
AIRMODE 模式下，飞行器将保持水平姿态，并尝试保持高度。在 AIRMODE 模式下，飞行器将保持水平姿态，并尝试保持高度。
```

AltHold | | | | | | | |--|--|--|--|--|--| | | | | | | | |--|--|--|--|--|--|

AltHold ☐ **Altitude Hold** ☐ ☐ ☐ ☐ **Stabilize** ☐

rangefinder[]



- □□ / □□□□□□□□ Stabilize □□□
- □□□□□□□□□□
- □□□□□□□□□□ / □□□□□□ / □□□□□□□□□□□□



Loiter □ PosHold□

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·  [altholdmode](#) · CC BY-SA 3.0

Auto ☐ ☐ ☐ ☐ ☐ ☐

Auto



- 
- GPS /  Failsafe 
-  Loiter/Brake/RTL 



Brake ☐☐☐☐☐☐





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P NE JERK

, 15 30











<https://youtu.be/-Db4u8LJE5w> (□ (□)).

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	url 📄 :	📄 =103

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 (

)

() 10, 0 2000). 4.6 , ();
 .
















```

0x00000000 . 0x00000000 RC 6, 0 0x00000000 39,
0x00000000 : 0x00000000 0 0 bitmask 0 (0x00000000)
0x00000000 .

```



 0 , : 1.

- [illegible]



SystemID

$$[\begin{array}{|c|} \hline \square \\ \hline \end{array} \begin{array}{|c|} \hline \square \\ \hline \end{array} \begin{array}{|c|} \hline \square \\ \hline \end{array} \begin{array}{|c|} \hline \square \\ \hline \end{array} \begin{array}{|c|} \hline \square \\ \hline \end{array} \begin{array}{|c|} \hline \square \\ \hline \end{array} \begin{array}{|c|} \hline \square \\ \hline \end{array}] = "[\begin{array}{|c|} \hline \square \\ \hline \end{array} \begin{array}{|c|} \hline \square \\ \hline \end{array}], [\begin{array}{|c|} \hline \square \\ \hline \end{array} \begin{array}{|c|} \hline \square \\ \hline \end{array} \begin{array}{|c|} \hline \square \\ \hline \end{array} \begin{array}{|c|} \hline \square \\ \hline \end{array}]".$$
$$[\begin{array}{|c|c|c|c|} \hline & & & \\ \hline \end{array}] = [\begin{array}{|c|c|} \hline & \\ \hline \end{array}].$$


-  grandparents 
- 
- 

, . ,
 , . **SID AXIS ()** .
 .



Diagram illustrating the structure of a 16-bit instruction:

The instruction is divided into three main fields:

- Op (Operation):** 4 bits, represented by the first four boxes.
- RD (Register):** 4 bits, represented by the next four boxes.
- Imm (Immediate):** 8 bits, represented by the final eight boxes.

The Imm field is further detailed as:

- Imm[7:4]:** 4 bits, the upper half of the immediate value.
- Imm[3:0]:** 4 bits, the lower half of the immediate value.

The Imm field is also associated with the **Plane** identifier.



VTOL, ID, qstabilize, qhover, qloiter, Guided, FBWA, Circle, Cruis, Loiter, Au, ID, Aux Switch.

☐ ☐ ☐ ☐ ☐ ☐ ☐ ☐
 Aux ☐ RCx ☐ ☐ ☐ 184 ☐ / ☐ ☐ ☐ ☐



XXXXXXXXXXXXXXXXXXXX :

[/] [= "cop " .



XXXXXXXXXX ,XXXXXXXXXXXXXXXXXXXX .
XXXXXXXXXXXXXXXXXXXX :

“

- XXXX grandparentsXXXXXXXXXX
- XXXXXXXXXXXXX
- XXXXXXXXXXXXX

XXXXXXXXXXXXXXXXXXXX ,XXX . XXXXXXXXXXXXX ,
XXXXXXXXXXXXXXXXXXXX ,XXXXXXXXXX . XXX **SID AXIS ()** .XXX
XXXXXXXXXXXX XXXXXXXXXXXXXXX ,XXXXXXXXXXXXXXXXXXXX STABILIZE
XXX . XXXXXXXXXXXXXXX ,XXXXXXXXXX ,XXXXXXXXXX .
XXXXXXXXXXXXXXXXXXXX .

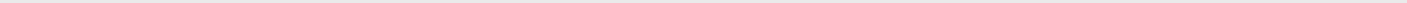


SID AXIS () .XXX ,XXXXXXXXXXXXXXXXXXXX ,XXXXXXXXXX
XXXXXXXXXXXX ,XXXXXXXXXX ,XXXXXXXXXXXXXXXXXXXX .



XXXXXXXXXXXXXXXXXXXX :

[/]



Drift

XXXXXXXXXXXXXXXXXXXX

XXXXXXXXXX



- Drift Mode XXXXXXXXXXXX, XXXXX XXXXXXXXXXXX
- XXXXXXXX " w " " Pitch " XXXXX " " " jaw " " pitch " , " " " XXX , " " XXX XXXXX XXXXX XXXXX 2XXX , XXXXXXXX
- XXXXXXXX ** XXXX **

(XXXXXXXXXX). <https://youtu.be/0mdk2-sNXmg>

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:

100%



- XXXXX " " (XXX 2) XXXXXXXX Pitch Yaw.
- XXXXXXXX, XXXXXXXX XXX .
- XXXXXXXX XXXXXXXX (XXX) XXXXXXXX
- XXXXXXXX XXXX
- XXXXXXXX, XX XXXXXXXX
- XXXX, XXXX XXXXXXXX, XXXXXXXX XXX
- XXXXXXXXXX (XXX) XXXX .
- XXXX XXXXX XXXXXXXXXXXXXXXX .
- XXXXXXXX, XXXXXXXX XXXXXXXX (XXXXXXXXXXXXX).
- XXXXXXXXXX XXXXXXXX XXXXXXXXXX XXXX
- XXXXXXXXXX (**MOT SPIN MIN**), XXXX XXXXXXXXXX XXXX
- XXXXXXXX : XXXXXXXXXX : XXXXXXXXXX :
XXXXXXX : XXXXXXXXXX : XXXXXXXXXX :
XXXXXXX : XXXXXXXXXX : XXXXXXXXXX :
XXXXXXX : XX

-  GPS    **FS EKF ACTION** 
-  

--	--	--	--	--

- FPV  ,  ,                         
-                              
-                              
-                              

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-  
-   , 



Copter [] [] [] [] [] [] Flight Modes[] [] [] [] [] [] [] [] [] [] [] [] [] [] [] []

1. **Stabilize** — 
2. **AltHold** — 
3. **Loiter / PosHold** — 
4. **RTL / Land / Auto** — 

□□ □□□□□□□□ Stabilize□□ AltHold□□ Loiter□ RTL□□□□□□□□ /

Flip

（ACRO/ALTHOLD/STABILILZE. FLIP ）
 , , , ,
 ** , FLIP ,
 .

10 !

- FLIP .
- ROLL LEFT, RC Pitch , ,
 . RC Pitch , RC ROLL , .
 - , !
 - , .
 - (, Aux Switch , FLIP .
 FLIP , , , ,

FlowHold

```
FlowHold[ ] ** [ ] ** [ ] , [ ] GPS,[ ] Lidar. [ ]
```

```
**rangefinder**[ ] **Loiter**[ ] .
```

<https://youtu.be/SSikG58cDk> □□□□ ,□□ .

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1	2
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, 

, 
****** 
****** ,

****Loiter****

FlowHold[2] PosHold[3] , [8] [16]
[8] , [16] .

 Lidar, ,
, .

 FlowHold : Flow.

- **    ** 
- ** FHLD FILT HZ () ** 
- **FHLD FLOW MAX ** ( m/s)
- ** FHLD+UAL  **  
- FlowHold  AltHold 
- **FHLD Y P**, **FHLD Y Alfredo I**, **FHL ** **FHLD Y FILT HZ **


Follow

<https://youtu.be/g9SkK0lhRk> (()).



Follow, ()

DroneBridge ESP32 Mult-Vehicle Flying

MAVLink, .lua

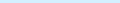
Follow :

- **FOLL ENBAL : 1
- **FOLL SYSID **: MAVLink ("0" " ") ID.
- **FOLL DIST MAX: , ô
- **FOLL OFS**, **FOLL OFS Y**, **FOLL OFS Z**: 3D ()
- ** FOLL OFS TYPE **: , 0; 1,
- **FOLL YAW BEHAVE :
- **FOLL POPS P** : (**WP SPD)
- **FOLL ALT TYPE **: .
- (**O**): 0 " 1"
- **F ACCEL NE **, **FOLL JERK NE **: ,
- **FOLL ACCEL D **, **FOLL JERK D **: ,
- **FOLL ACCEL H **, **FOLL JERK H **:
- **FOLL TIMEOUT **: . ,
- **WP SPD** **WP SPD UP** **WP SPD DN** **WP ACC** **WP ACC Z**: :



**FOLL ALT  **   ,  

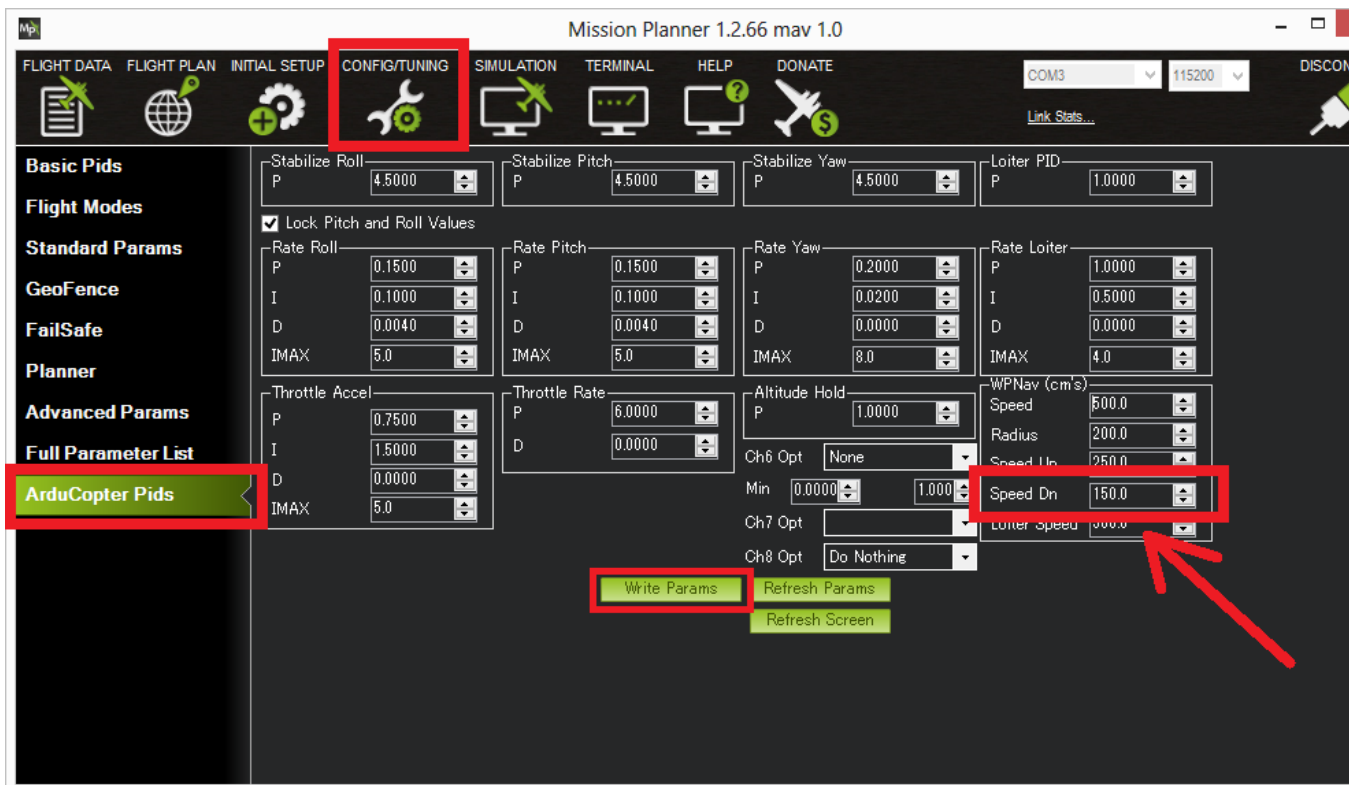

- 1"(,) . . EKF (. EK3
SRCx POPSZ = GPS ,
.
- "0"() : "0"().
 ,
 ,
- "3"(terrain) ,
 , () ,
 , ,

 ,  ArduPilot   
   , "  "  

Land

□□ :

- □□□ (□□□□□□) **2017-09-21). Land SPD High MS**,□□□□ , (□ ****WP SPD DN**** □□□)□□□□□□□□□□ .
- □□□□□□□□□□ □□□□ □□ □ yaw □ ,□□ **LAND REPOSITION **** □□□□ **"0"**,



Heli Heli , "Heli" "Throttle
". . , **H COL LAND MIN**
AUTOR đó, ,
Alabamaming a de*. :
,

☐ Whow Whites(Whow) ,

☐ LGR WOW PIN,

- 

Alt Hold, Loiter, NAV Land RTL
()
, () :

-  Andy, I. 
- ,  
-  .

Loiter

Loiter / GPS

GPS

Emagnetic



-
-
- AltHold

Loiter

PosHold

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[illegible]

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[illegible]

, PosHold GPS ,** ** **

http http http http http http http http http http http http http http http http http
http http http http http □ http http http http http http http http http http http
http http http http http http http http http http http http http s s http http s s http s http s
http http s http s http s s

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url □□ :	□□ =117



-  ,  45° (  **ATC ANGLE MAX**
)

-
- Mission Planner 1.2.92.2 build 1.15117.35558
- FLIGHT DATA FLIGHT PLAN INITIAL SETUP CONFIG/TUNING SIMULATION TERMINAL HELP DONATE
- COM15 115200 DISCONNECT Link Stats...
- 345 N 15 30 41E 60 75 E
- 100% 20:19:55
- DISARMED
- AS 0.1 GS 0.1 Stabilize 0>0
- GPS: 3D Fix
- Quick Actions Gauges Status Servo Telemetry Logs DataFlash Logs Scripts
- Altitude (m) GroundSpeed (m/s)
- 0.44 0.06
- Gps HDOP 2.69
- Display This
- | | | | | | | | | | |
|---|---|-----------------------------------|---------------------------------|-------------------------------------|---|--|--|---------------------------------------|--------------------------------------|
| ☐ roll | ☐ altd1000 | ☐ ay | ☐ gyroeq | ☐ ch1out | ☐ nav_pitch | ☐ distTraveled | ☐ HomeAlt | ☐ accel_cal_y | ☐ remnoise |
| ☐ pitch | ☐ altd100 | ☐ az | ☐ rxrssi | ☐ ch2out | ☐ nav_bearing | ☐ timeInAir | ☐ DistToHome | ☐ accel_cal_z | ☐ localsnrb |
| ☐ yaw | ☐ airspeed | ☐ gx | ☐ ch1in | ☐ ch3out | ☐ target_bearing | ☐ turnrate | ☐ ELToMAV | ☐ sonarrange | ☐ remotesnrb |
| ☐ groundcourse | ☐ targetairspeed | ☐ gy | ☐ ch2in | ☐ ch4out | ☐ wp_dist | ☐ radius | ☐ AZToMAV | ☐ sonarvoltage | ☐ DistRSSIRem |
| ☐ alt | ☐ asratio | ☐ gz | ☐ ch3in | ☐ ch5out | ☐ alt_error | ☐ targetalt100 | ☐ press_abs | ☐ freemem | ☐ hwvoltage |
| ☐ altasl | ☐ groundspeed | ☐ mx | ☐ ch4in | ☐ ch6out | ☐ ber_error | ☐ targetalt | ☐ mag_declination | ☐ load | |
| ☐ alttofssethome | ☐ verticalspeed | ☐ my | ☐ ch5in | ☐ ch7out | ☐ aspd_error | ☐ battery_voltage | ☐ gyro_cal_x | ☐ brklevel | |
| ☐ epsstatus | ☐ wind_dir | ☐ mz | ☐ ch6in | ☐ ch8out | ☐ xtrack_error | ☐ battery_remain | ☐ gyro_cal_y | ☐ rssi | |
| ☒ gpshdop | ☐ wind_vel | ☐ magfield | ☐ ch7in | ☐ ch3percent | ☐ wpno | ☐ current | ☐ gyro_cal_z | ☐ remrssi | |
| ☐ satcount | ☐ ax | ☐ accelq | ☐ ch8in | ☐ nav_roll | ☐ climbrate | ☐ battery_usedm | ☐ accel_cal_x | ☐ noise | |
- GEO 36.324346 138.639283 0.44 Tuning Auto Pan Zoom 18.7

- PHLD BRK ANGLE (00)

Opera

• PHLD BRK 00 00 (08 = 8 0000) (00)

RTL□□□□□□

RTL□ Return To Launch□□□ □□□□□□□□ Home□□□□□□□□

□□

□ RTL □□□□

Home □□□□□□

GeoFence□□

Failsafe □□□□□□□□

Home□ GPS □□□□□□□□□□□□□□



- □□□□□□ RTL □□□□□□□□□□□□
- □□ Home□□□□ RTL_ALT_FINAL □□□□□□□□
- □□□□ /□□ Failsafe □□□□□□

□□□□□□ Home □□□□□□□□ RTL □ SmartRTL □□□□

Pilots roll command causes the vehicle to roll to it's right.





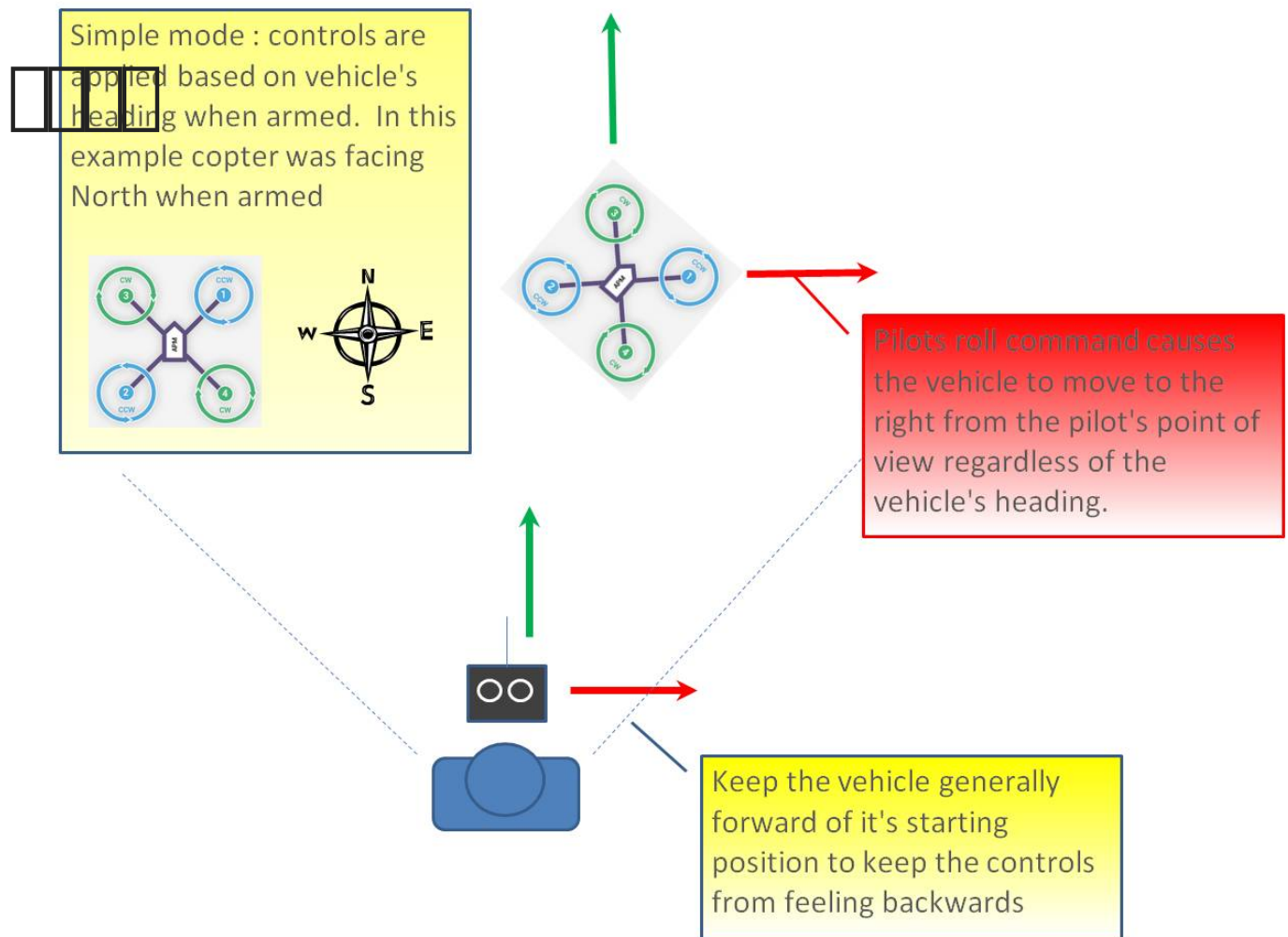


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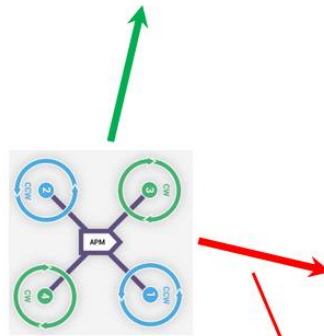
00000000 "0000" "00 ,000000 {\\fn0000
\\fs20\\bord1\\shad1\\lcHE0E0E0\\cH0000000}000000 ,00 19. 00000000 ,00000000
0000 00 ,00000000 , 00000000 0000 ,00000000 ,00000000 0000 0000
00000000 yaw 00000000 ,00 00000000 00000000

```

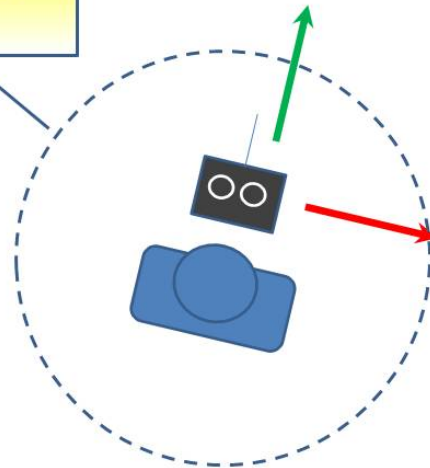




Super Simple mode : controls are applied based on the vehicle's GPS position relative to home.



Pilot vs vehicle control angles are not updated within 10m of home

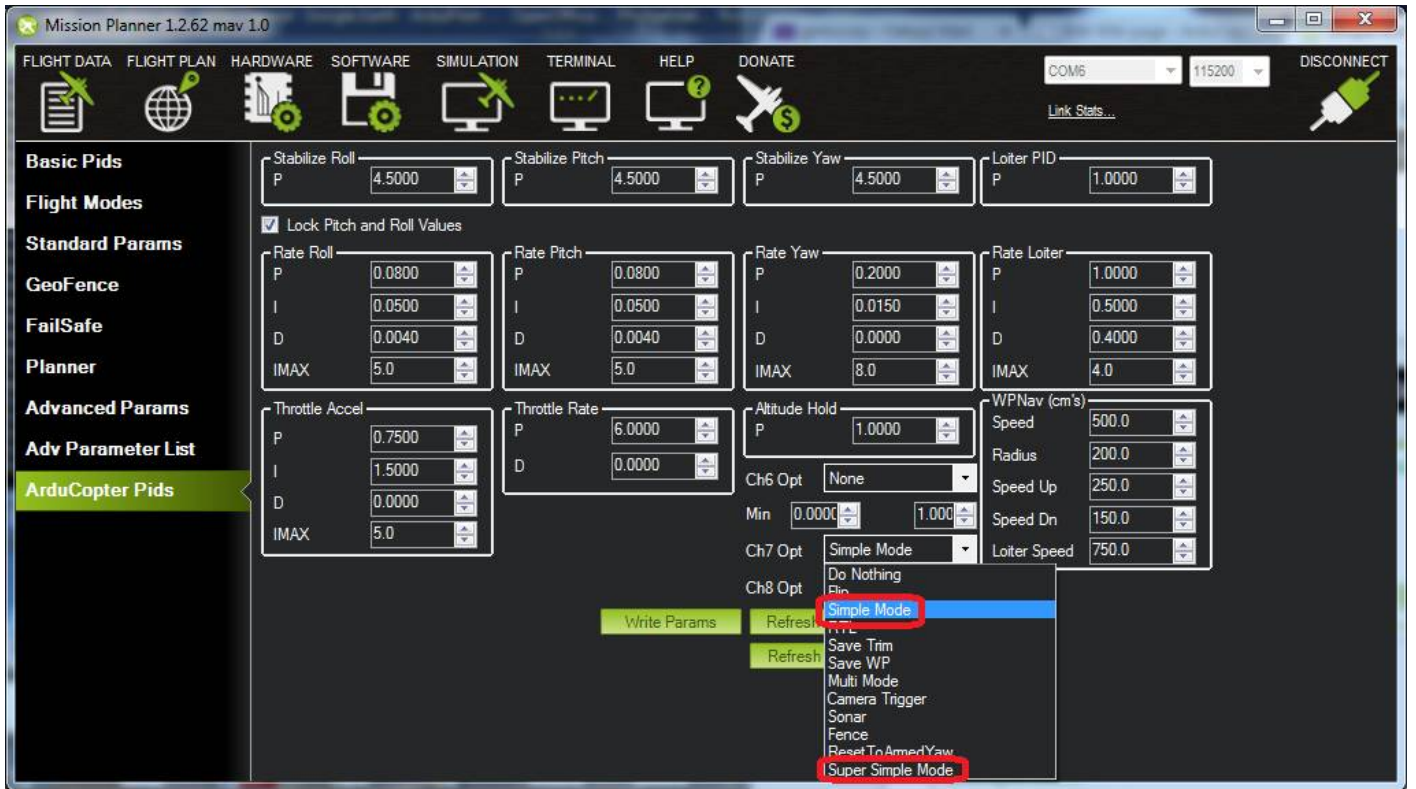


Pilots roll command causes the vehicle to move to the right from the pilot's point of view regardless of the vehicle's heading and even if the vehicle moves behind the pilot.

The vehicle's GPS position is used to calculate the distance from the home point. If the distance is greater than 10 meters, the vehicle's heading is updated. If the distance is less than 10 meters, the vehicle's heading is not updated. This is because the vehicle's heading is not updated within 10 meters of home.

The vehicle's roll command causes the vehicle to move to the right from the pilot's point of view regardless of the vehicle's heading and even if the vehicle moves behind the pilot.





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SmartRTL

<https://youtu.be/gXfBmFnJEU> (()).



Smart RTL, "Smart", ,

(LED), SmartRTL .
,"SmartRTL : " .

, " "(
) "prun "() . (),
,"SmartRTL : uful full" HUD , .

SmartRTL 3 , **SRTL ACCURACY** 1 , ,
10 / , 3.3 . 50 , **SRTL
ACCURACY** **SRT Board ACCURACY** ,
 .

SmartRTL. ,

**FS GCS enable ** **FS THR enable ** 4 5, SmartRTL->RTL SmartRTL>
SmartRTL, RTL(4) Land(5)

SmartRTL Failsaces : **BATT FS CRT ACT **, **BATT FS LOW ACT(: ** **BATT2
FS LOW ACT** **BATT2 FS C ACT**

SmartRTL

- **RTL SPEED** (/). , , **WP
SPD** .

The diagram illustrates the decomposition of 100 into 10 tens and 10 ones. At the top, there are two 100-unit blocks. Below them, the first 100-unit block is decomposed into 10 tens (represented by 10 vertical bars) and 10 ones (represented by 10 small squares). The second 100-unit block is also decomposed into 10 tens and 10 ones. The tens are arranged in two groups of five, and the ones are arranged in two groups of five. This visualizes the concept that 100 is equal to 10 tens and 10 ones.

- FPV , ,
- , ya
- 30 (: **ATC ANGLE MAX**)
- **DZ** 2.5m/s(**PLOT SP** **PILOT SPD DN** (()).
) **PLOT ACC Z.**

Stabilize

[illegible]

Roll [] [] [] [] []

Pitch

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AltHold ☐ ☐ ☐ ☐

Loiter

☐ Stabilize ☐

GPS

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RTL

3D GPS ☐☐☐ HDOP ☐☐☐☐HDOP

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Stabilize

[illegible]

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☐ ☐ ☐ ☐ AltHold ☐ Loiter ☐ Acro ☐ Sport


[stabilize-mode](https://creativecommons.org/licenses/by-sa/3.0/) · CC BY-SA 3.0

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(GPS,
, Beacon, etc.).



1. `int`
2. `int`
3. `int` GPS `int`
4. `int` `int` (`int`) `int` .
5. `int` , `int` (`int` 50 `int` / `int` , `int` 5 `int` / `int`)
6. `int` , `int` Loiter(`int`), `int`











- ****THROW TYPE****:    0,  1 ,  10 

- <https://youtu.be/ZnEFcJx1qko> (□□ (□□)).



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The diagram illustrates a two-layer neural network architecture. The top layer (blue) consists of 2 input nodes, 10 hidden nodes, and 1 output node. The bottom layer (orange) consists of 2 input nodes, 10 hidden nodes, 5 hidden nodes, and 1 output node labeled SITL. Connections are shown between layers.

[illegible]









ArduCopter 2009 10 1

[illegible]

- [illegible]

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```
../images/autorotation_phases.png
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“ ../images/autorotation_inflow_angles.png
```

1. 在 2019 年 12 月 31 日，公司应收账款余额为 100 万元，坏账准备余额为 10 万元。2020 年 1 月 1 日，公司应收账款余额为 120 万元，坏账准备余额为 12 万元。2020 年 1 月 1 日至 2020 年 12 月 31 日，公司应收账款余额为 150 万元，坏账准备余额为 15 万元。2020 年 12 月 31 日，公司应收账款余额为 180 万元，坏账准备余额为 18 万元。



Diagram illustrating the addition of three numbers using base ten blocks:

- Number 1: 14 (1 ten rod and 4 one units)
- Number 2: 26 (2 ten rods and 6 one units)
- Number 3: 12 (1 ten rod and 2 one units)
- Sum: 52 (5 ten rods and 2 one units)



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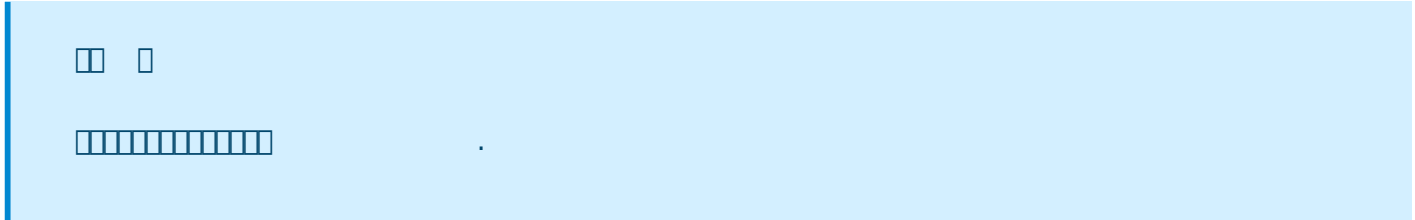
“ ../images/autorotation_switchology.png



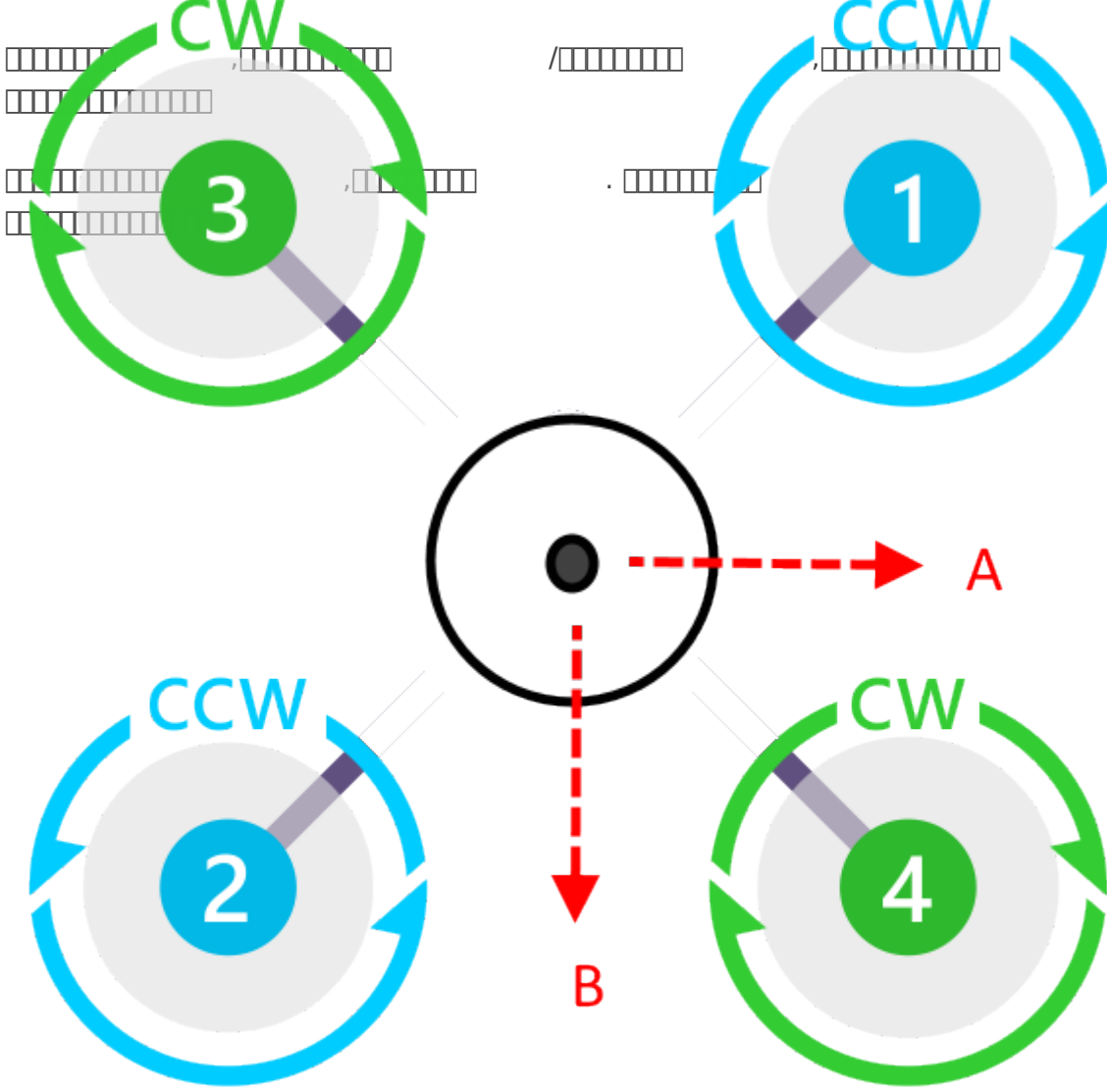
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Turtle

Turtle Mode , ** RC () . Turtle Copter , , .



DSHOT ESC , DSHOT ESC (). MOT PWM DSHOT DSHOT



Moving stick towards A, spins motors 1& 4
Towards B, spins motors 2 & 4

ZigZag

ZigZag, ,

<https://youtu.be/qNmLX4QmPU> (()).

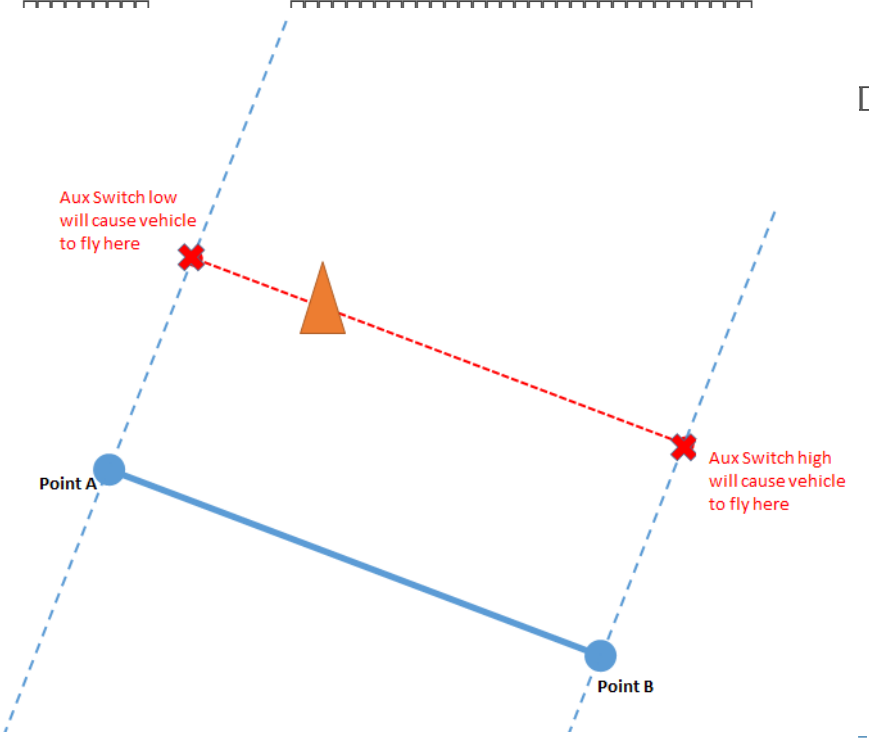
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100%

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- 61 /"ZigZag Sa 20.WP"(**RC7 OPTION ** = 61).
- . Loiter
- ()
- ,
- 666 () . ,



ZigZag Loiter ** . , **LOIT SPEED MS.

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****WP SPD..**

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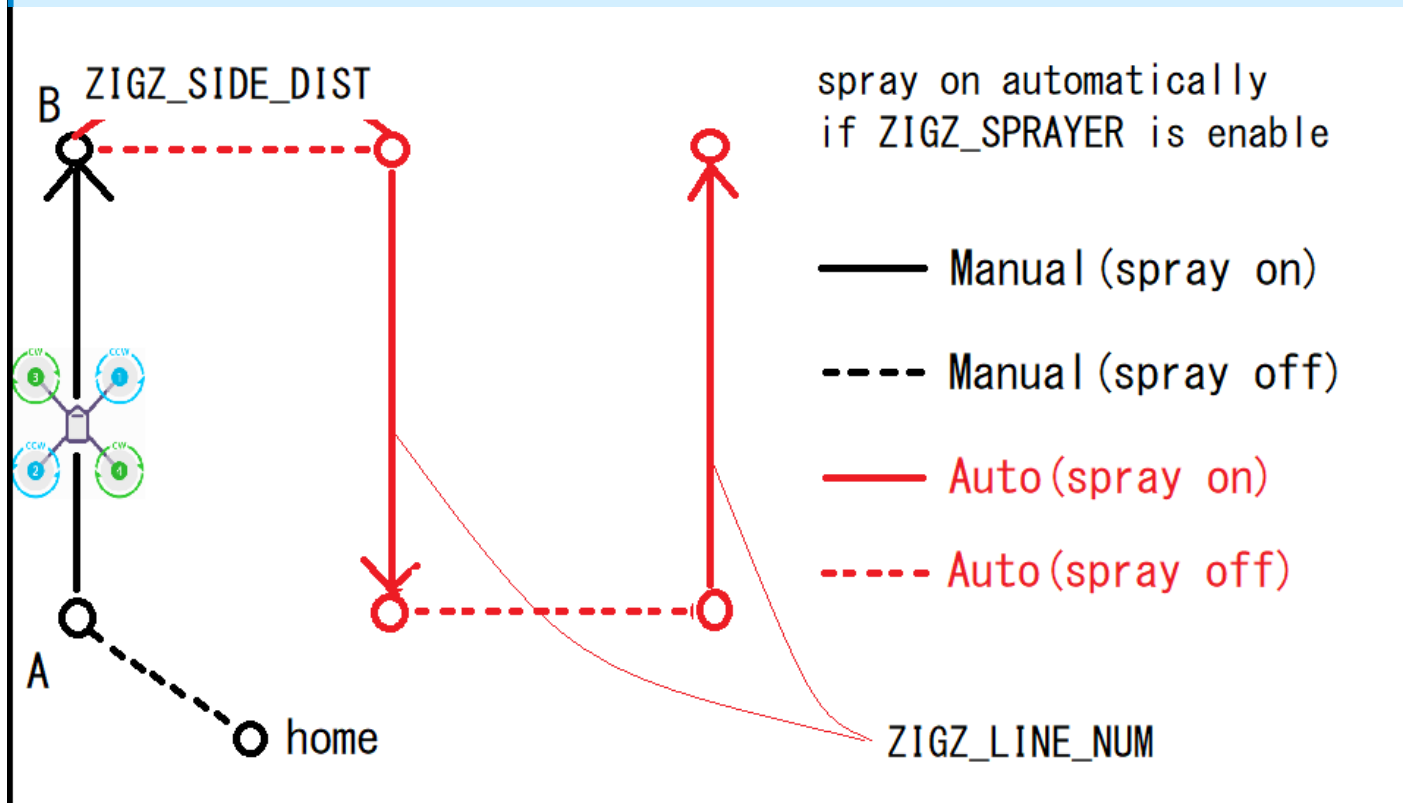
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-4.1.0□□□

11

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[illegible]

1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19	20	21	22	23	24	25	26	27	28	29	30	31	32	33	34	35	36	37	38	39	40	41	42	43	44	45	46	47	48	49	50	51	52	53	54	55	56	57	58	59	60	61	62	63	64	65	66	67	68	69	70	71	72	73	74	75	76	77	78	79	80	81	82	83	84	85	86	87	88	89	90	91	92	93	94	95	96	97	98	99	100
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-  ,  ZigZagWP B .
-  ZigZag  ,  
-  ,   **ZIG**  ,  ,  **ZigZagWP**  **WP DELAY**  **ZIG** 



ZIGZ 
NUMtimes (-1 =  ,  , = 0

 , ).

- ZigZ

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