



```
uint8_t *data = new uint8_t[100]; // 100 bytes of data  
// ...  
ya(gps.yaw, gps.roll, gps.pitch)
```

 . , ,
 .  ,  **  ** 



, , 3D gps . ,
 , 3D gps .

A 10x20 grid of small squares. The first 8 rows are completely filled with blue squares. The 9th row has 18 blue squares, and the 10th row has 8 blue squares. This represents a total of 168 blue squares.

```
ArduPilot["altitude"] = altitude,
["roll"] = roll,
["pitch"] = pitch,
["yaw"] = yaw,
["inclinacion"] = inclination,
["roll_rate"] = roll_rate,
```



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Install Firmware

>> Mandatory Hardware

Accel Calibration

Compass

Radio Calibration

Servo Output

ESC Calibration

Flight Modes

FailSafe

HW ID

ADSB

>> Optional Hardware

>> Advanced

Compass Priority

Set the Compass Priority by reordering the compasses in the table below (Highest at the top)

	Priority	DevID	BusType	Bus	Address	DevType	Missing	External	Orientation	
	1	97539	UAVCAN	0	125	SENSOR_ID#1	☐	☒	None	▼
	2	131874	SPI	4	3	LSM303D	☒	☐		▼
	3	263178	SPI	1	4	AK8963	☐	☐	None	▼
	4	97283	UAVCAN	0	124	SENSOR_ID#1	☐	☐		▼
	5	97795	UAVCAN	0	126	SENSOR_ID#1	☐	☐		▼
	6	98051	UAVCAN	0	127	SENSOR_ID#1	☐	☐		▼

Do you want to disable any of the first 3 compasses?

☒ Use Compass 1 ☒ Use Compass 2 ☒ Use Compass 3

Remove Missing

☐ Automatically learn offsets

A reboot is required to adjust the ordering.

Reboot

A mag calibration is required to remap the above changes.

Onboard Mag Calibration

Start Accept Cancel

Mag 1

Mag 2

Mag 3

Fitness

Default

 Relax fitness if calibration fails

Large Vehicle MagCal

:

"

"

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,

：

• “ Onboard Mag ” “ ”

• 360

• 6



- ,
- 3 " " ,

：

- " " , () .
- Revolution imple, " " "Fitness" "
- ** COMPAS OFFFS MAX ** 850 2000 3000
- , ,

RC

RC , USB .

RC "171".

MagCal

[illegible]

<https://youtu.be/DmsueBS0J3E> ([📺](#) ([📺](#))).



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