



```
[name = "sub"]. . :Sub[...],[...] ROV[...].
[...](RC),[...] MAVLink[...],
[...]. [...],[...] [...][...]
[...][...]

[... ArduPilot[...]. [...].
[... ArduPilot[...]
```

[../..../images/block-diagram.jpg_](#)



```
[...],[...],
[...],[...],[...].
```



```
[...] MAVLink[...],
[... Roll/Pitch[...]/Yaw[...],[...],
[...]. Roll/Pitch/Yaw/Throttle
[... RCMAP x [...][...]
RCx_FUNCTION parameters.
```

Outputs

Outputs are provided to activate servos, motors, relays, etc. to control the vehicle. Any autopilot output can be assigned the desired vehicle control output function via the `SERVOn_FUNCTION` parameters. Note that outputs do NOT necessarily correspond to any RC input, unless their function is set to RCPassThru.

Sensors

Attitude, position, power system monitoring, and vehicle speed are provided by sensor inputs to the autopilot. All ArduPilot compatible autopilots have at least one or more accelerometers, baros, and gyros integrated onboard. Typically a GPS, and often, a Compass sensor is required. Usually these are provided externally. Some controllers have multiple instances of sensors for redundancy, a key feature of the ArduPilot software. Many sensors require a one-time calibration during the Mandatory Hardware setup step.

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[copywiki destination="plane,copter,rover,sub"]
```



ArduPilot Copter Simple Overview of ArduPilot Operation · CC BY-SA 3.0

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Admin 2026-10-09 14:41:06 UTC

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