

Announcements about upgrade DoS multi-rotor firmware V 2.1

Firmware V2.1 Update Log:

- 1、 Add GPS Hovering mode and Auto Return To Launch (RTL) mode
- 2、 To improve the fixed altitude flight effect

DoS firmware V2.1 add the GPS function and Camera Gimbal Stabilization control function,so the “FY-DOS-COPTER-SETTING V1.2” software add the Navigation control and Camera Gimbal Stabilization control parameters.Please noticed that,when you upgrade firmware to V2.1 from V2.0,you should set these two parameters to default before any flight test.(But upgarde firmware V2.1 from fixed wing aircraft firmware all the parameters will automatic set to default)

DoS multi-rotor firmware V2.1 default parameters:

The screenshot shows the 'FY-DOS-COPTER-SETTING V1.2' software window. It features a 'Port' section with 'COM5' and '19200' selected, and 'Auto Connect' checked. A 'Read and Write' section includes 'Read All' and 'Save All' buttons. The 'Install Setting' section displays a quadcopter diagram with 'DoS' labels on the arms. The 'Mixer Type' section shows 'QUAD X' selected. The 'Parameters Setting' section contains a table of default values for Roll, Pitch, Yaw, Vertical, and NAV parameters. The 'Gimbal Gain' section shows 'Roll 50' and 'Pitch 50'. The 'Gimbal Reverse' section shows 'Roll' and 'Pitch' both set to 'x'. The 'Gimbal Neutral' section shows 'Roll 1520' and 'Pitch 1520'. A status bar at the bottom indicates 'Read Pantilt Parameter Done!'.

Parameter	RC Gain	Control P	Control I
Roll:	30	35	10
Pitch:	30	35	10
Yaw:	30	40	10
Vertical:		50	20
NAV:		6	10

Please set the navigation control and Camera Gimbal Stabilization control parameters to default:

(1) Navigation control parameters

NAV:	Control P	6	Control I	10
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(2) Camera Gimbal Stabilization control parameters

Gimbal Gain		Gimbal Reverse		Gimbal Neutral	
Roll	50	Pitch	50	Roll	1520
				Pitch	1520