

Press 'q' to quit

Arduplane is running

< Stop >

Choose your vehicle

< copter >

< plane >

< rover >

< sub >

Choose your version

< 4.0 >

Choose your frame

< arduplane >

On boot:

< enable >

< disable >

Ardupilot:

< start >

< stop >

Vendor: Emlid Limited

Product: Navio 2

Issue: Emlid 2020-09-22 716f472abba15f9ec2b6fc51f498538e3c041d42

Kernel: 4.19.127-emlid-v7l+

RCIO firmware: 0xb9064332

emlidtool version: 1.0.8

Ardupilot Info

On boot enabled: ['arduplane']

Ardupilot isn't running

Press 'q' to quit

Arduplane is running

< Stop

Choose your vehicle

< copter

< plane

< rover

< sub

Choose your version

< 4.0

Choose your frame

< arduplane

On boot:

< enable

< disable

Ardupilot:

< start

< stop

< Apply

< Quit

You've successfully configured
plane with frame arduplane.
arduplane version: 4.0

Vendor: Emlid Limited

Product: Navio 2

Issue: Emlid 2020-09-22 716f472abba15f9ec2b6fc51f49

Kernel: 4.19.127-emlid-v7l+

RCIO firmware: 0xb9064332

emlidtool version: 1.0.8

Ardupilot Info

On boot enabled: ['arduplane']

Arduplane - active (running)

Version: arduplane-4.0

Frame: arduplane

Tests

Could not run tests because ArduPilot is running

ESC Calibration (AC3.3+)

Calibrate ESCs

Remove Props!
After pushing this button:
-Disconnect USB and battery
-Plug in battery
-when LEDs flash, push Saftey Switch (if present)
-ESCs should beep as they are calibrated
- restart flight controller normally

ESC Type:

Output PWM Min

Leave as 0 to use RX input range

Output PWM Max

Leave as 0 to use RX input range

Spin when Armed

speed when motors are armed but throttle is at zero (idle)

Spin minimum

minimum speed of motors while in flight (slightly higher than "Spin when Armed")

Spin Maximum

maximum speed of motors while in flight (almost all escs have a deadzone at the top)

Set param error. Please ensure your version is AC3.3+.

OK

```
pi@navio:~ $ sudo su
root@navio:/home/pi# sudo apt-get update && sudo apt-get dist-upgrade
Hit:1 http://archive.raspberrypi.org/debian buster InRelease
Get:2 http://files.emlid.com/navio2/debian buster InRelease [2,213 B]
Hit:3 http://raspbian.raspberrypi.org/raspbian buster InRelease
Hit:4 http://packages.ros.org/ros/ubuntu buster InRelease
Fetched 2,213 B in 2s (1,441 B/s)
Reading package lists... Done
Reading package lists... Done
Building dependency tree
Reading state information... Done
Calculating upgrade... Done
The following packages were automatically installed and are no longer required:
  python-catkin-pkg-modules python-concurrent.futures python-osrf-pycommon python-pyparsing python-rosdistro-modules python-rospkg-modules
  python-trollius
Use 'sudo apt autoremove' to remove them.
0 upgraded, 0 newly installed, 0 to remove and 0 not upgraded.
root@navio:/home/pi#
```