

temp



Geo ref images	moved to dataflash tab	hex Mavlink decode	3D GYRO	Dis	No	Bad
Warning Manager	Create custom audio warnings	drivers clean	3D ACCEL	Dis	No	Bad
Follow Me	use a nmea gps to follow me	Toggle Safety Switch	3D MAG	Dis	No	Bad
NMEA	outputs the mav location in nmea	Message Interval	ABSOLUTE PRESSURE	Dis	No	Bad
MicroDrone	outputs the mav location in microdrone format	MAVLink Inspector	DIFFERENTIAL PRESSURE	Dis	No	Bad
Mavlink	mirrors the mavlink stream received by mp	Bootloader Upgrade	GPS	Dis	No	Bad
Param gen	regenerate the param info used inside mp	3D Map	OPTICAL FLOW	Dis	No	Bad
Lang Edit	translation language editor	decode HWID's	VISION POSITION	Dis	No	Bad
OSDVideo	overlay the hud into your recorded videos	parse packet bytes	LASER POSITION	Dis	No	Bad
Moving Base	show an extra icon on the map of your current location	adjust aircraft baro height	EXTERNAL GROUND TRUTH	Dis	No	Bad
Shp to Poly	convert shp file ot a polygon file	Lockup MAV	ANGULAR RATE CONTROL	Dis	No	Bad
Anon Log		DEM	ATTITUDE STABILIZATION	Dis	No	Bad
Swarm	multi mav swarm interface	logdownload scp	YAW POSITION	Dis	No	Bad
Follow the leader	follow the leader swarm	ReSort All logs	Z ALTITUDE CONTROL	Dis	No	Bad
MAVSerial pass	create a exclusive passthrough to the gps (port 500)	Custom GDAL	XY POSITION CONTROL	Dis	No	Bad
Start Remote df logger		sitl streamcombiner	MOTOR OUTPUTS	Dis	No	Bad
Sort TLogs	sort tlogs into there type and sysid directories	Param Restore	RC RECEIVER	Dis	No	Bad
rip all fw	download all current fw's	FFT	3D GYRO2	Dis	No	Bad
Inject GE	add custom imagery to mp	grab threads.txt	3D ACCEL2	Dis	No	Bad
Clear Custom Maps	wipe custom imagery	reboot pixhawk	3D MAG2	Dis	No	Bad
structtest	struct conversion speed test	QNH	GEOFENCE	Dis	No	Bad
DashWare	Create dashware date input file	Sequence Swarm	AHRS	Dis	No	Bad
arm and takeoff	quad: arm and takeoff	vlc	TERRAIN	Dis	No	Bad
gimbal test	run the gimbal pointing algo	Age Map Data	REVERSE MOTOR	Dis	No	Bad
map logs	create map jpg's for all tlogs in a dir	Split DFLog	LOGGING	Dis	No	Bad
logindex	tlog browser	signing	BATTERY	Dis	No	Bad
opticalflow calib	display the image data from the px4 optical flow sensor	extract gps inject	PROXIMITY	Dis	No	Bad
APJ Tool		Proximity				
mag calb log	get mag offsets from a log	Follow Swarm				
CoT	Outputs Cursor-on-Target	Manage Command List				
Force Accel Cal	Mark accel as cal'd after param restore	DFU Mode				
Force Compass Cal	Mark mag as cal'd after param restore					

DATA

PLAN

SETUP

CONFIG

SIMULATION

HELP

000

NW

330

345

0

15

30

NE

60

00:00:00

0%

00:00:00

10

5

0m/s

0

-5

-10

10

5

0m

0

-5

-10

AS 0.0m/s

GS 0.0m/s

Unknown

0m>0

Not Ready to Arm

EKF Vibe

GPS: No GPS

Quick

Actions

Messages

PreFlight

Gauges

Transponder

Status

Serv

Loiter_l

Do Action

Auto

Set Home Alt

100

Change Speed

0 (Hom

Set WP

Loiter

Restart Mission

100

Change Alt

STABIL

Set Mode

RTL

Raw Sensor View

100

Set Loiter Rad

Retract

Set Mount

Joystick

Arm/ Disarm

Clear Track

Message

Resume Mission

Abort Landing

ARDUPILOT

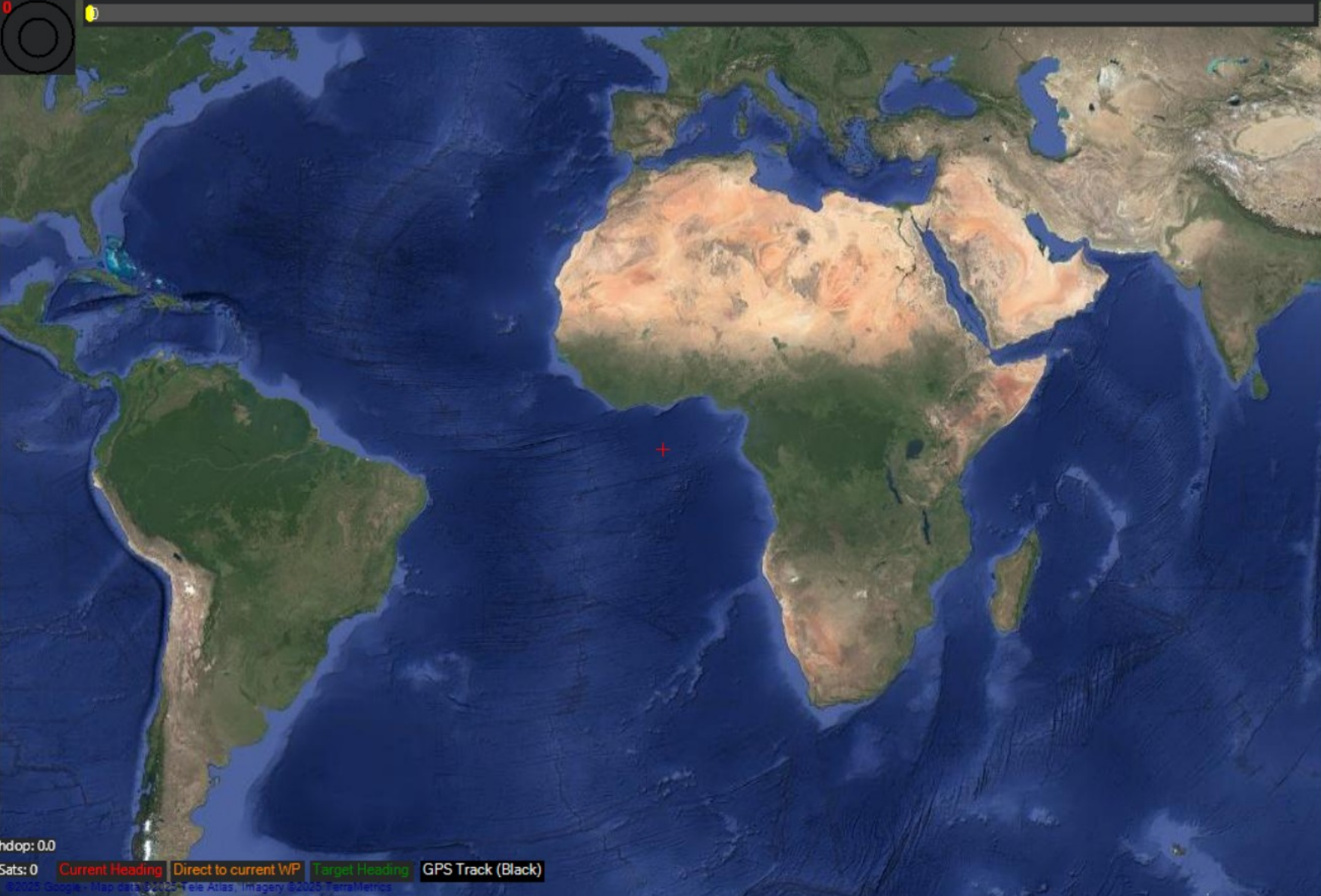
UDP

115200

CONNECT

Zoom

3.0



hdop: 0.0

Sats: 0

Current Heading

Direct to current WP

Target Heading

GPS Track (Black)

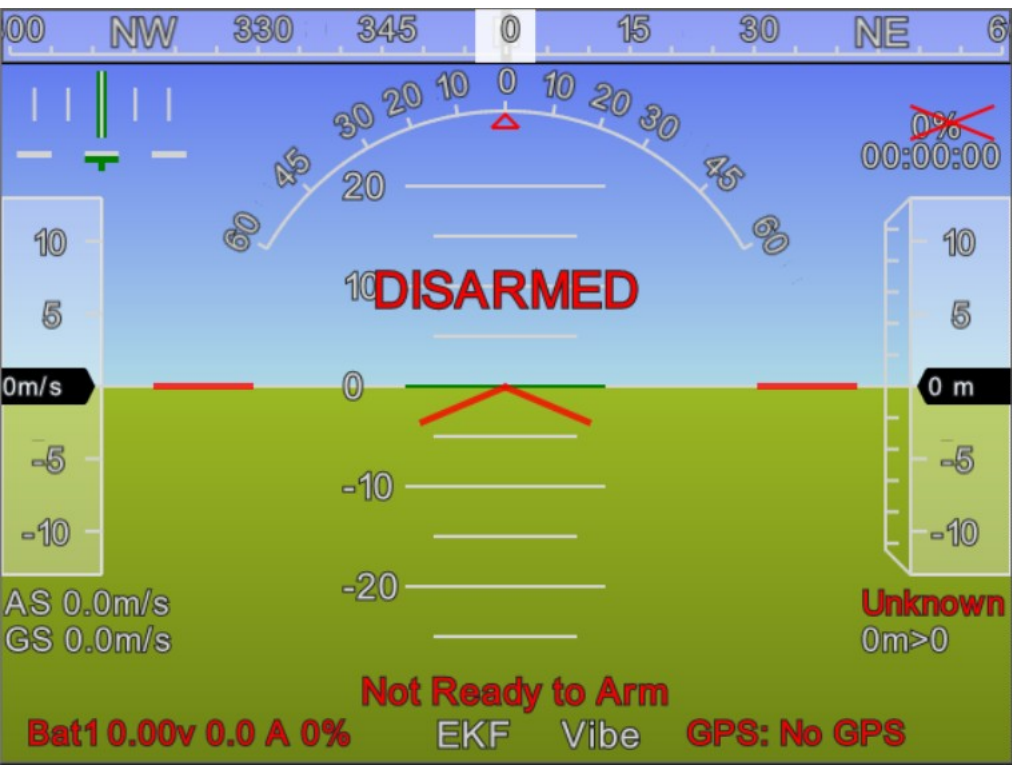
©2025 Google - Map data ©2025 OpenStreetMap contributors, Imagery ©2025 TerraMetrics

GEO

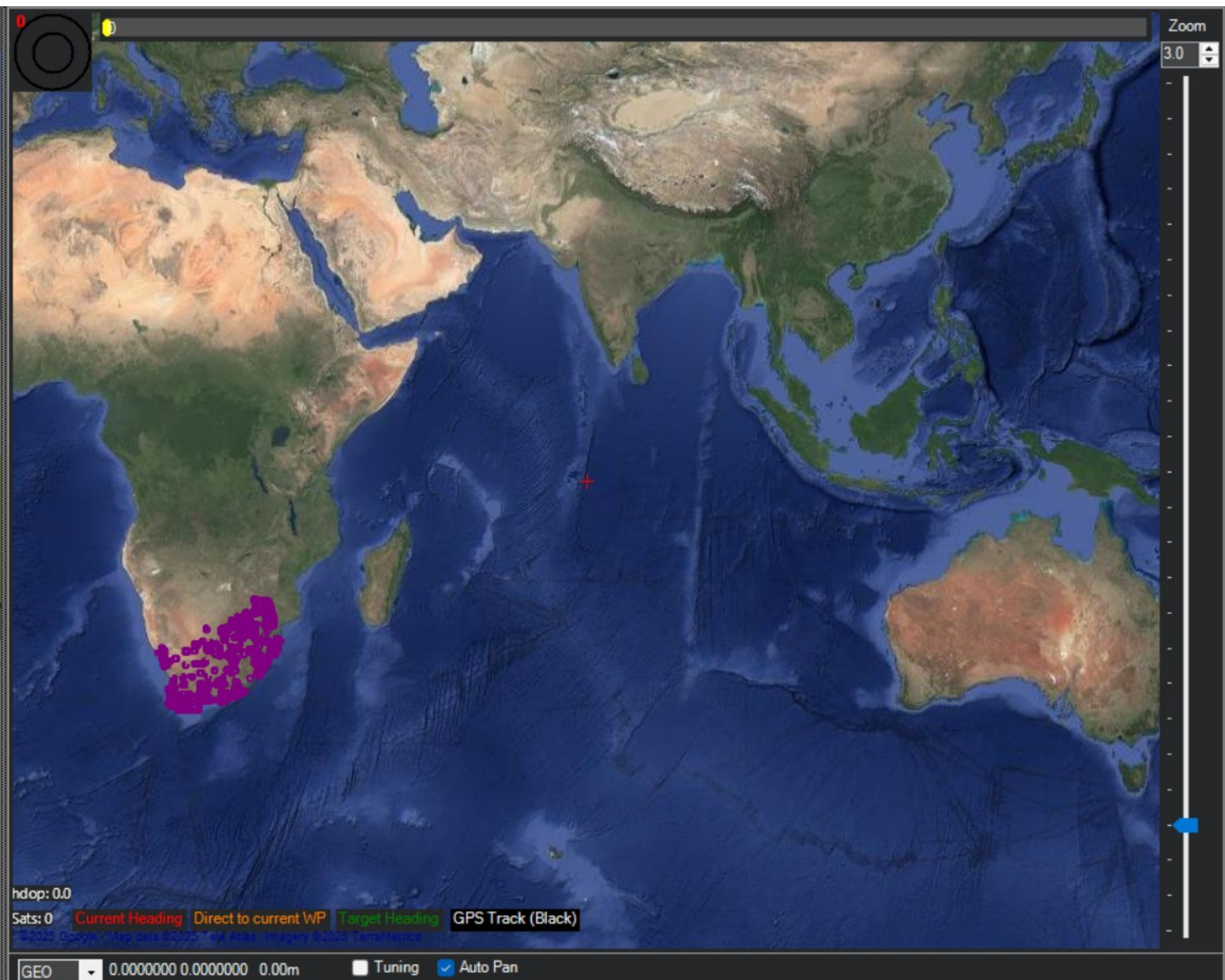
0.0000000 0.0000000 0.00m

Tuning

Auto Pan



Messages	PreFlight	Gauges	Transponder	Status	Servo/Relay	Lux Function	Scripts	Payload Control	Telemetry				
Low	Mid	High	Toggle	5	1100	1900	Low	Mid	High	Toggle	11	1100	1900
Low	Mid	High	Toggle	6	1100	1900	Low	Mid	High	Toggle	12	1100	1900
Low	Mid	High	Toggle	7	1100	1900	Low	Mid	High	Toggle	13	1100	1900
Low	Mid	High	Toggle	8	1100	1900	Low	Mid	High	Toggle	14	1100	1900
Low	Mid	High	Toggle	9	1100	1900	Low	Mid	High	Toggle	15	1100	1900
Low	Mid	High	Toggle	10	1100	1900	Low	Mid	High	Toggle	16	1100	1900
							Low	High	Toggle	Relay 1			



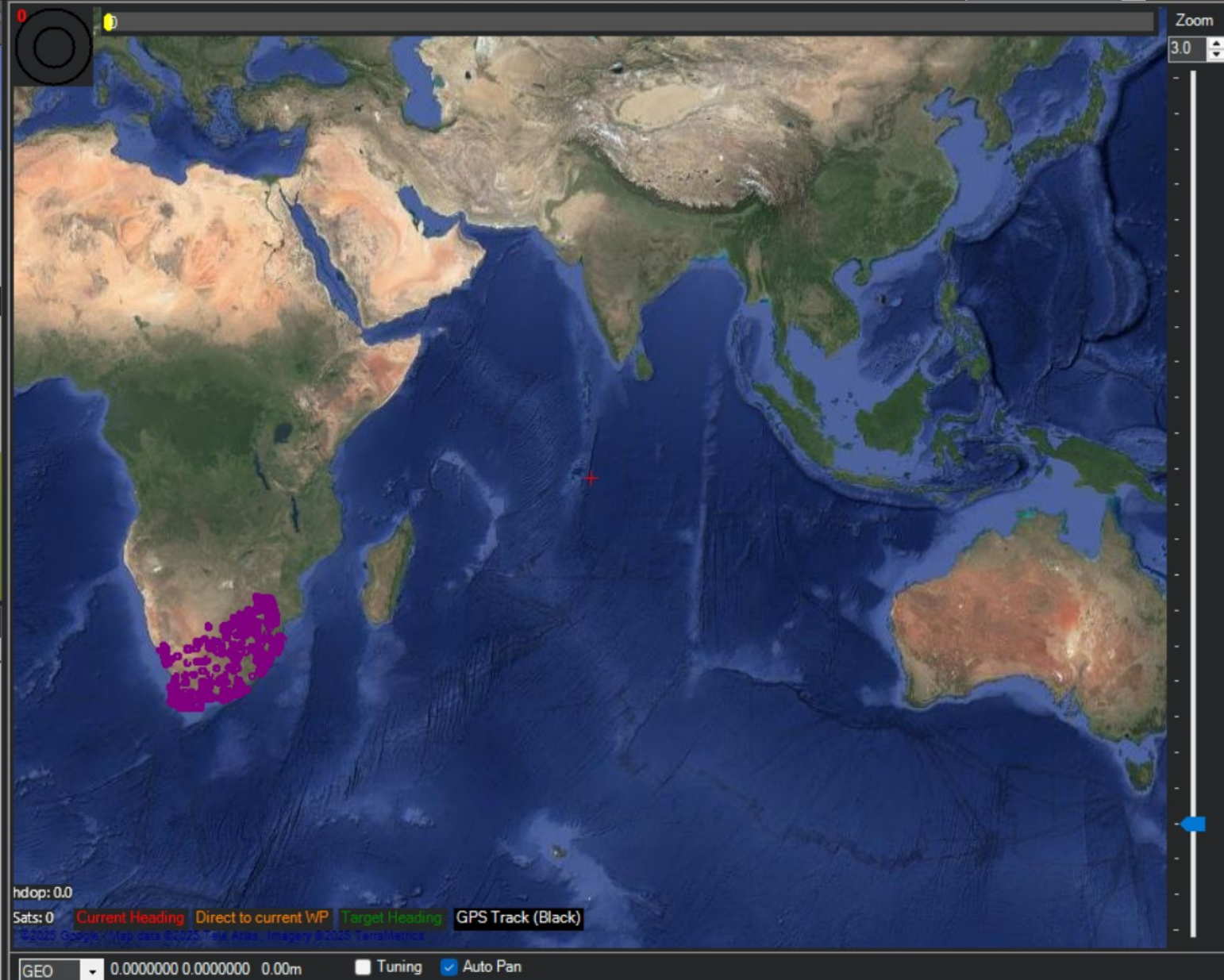


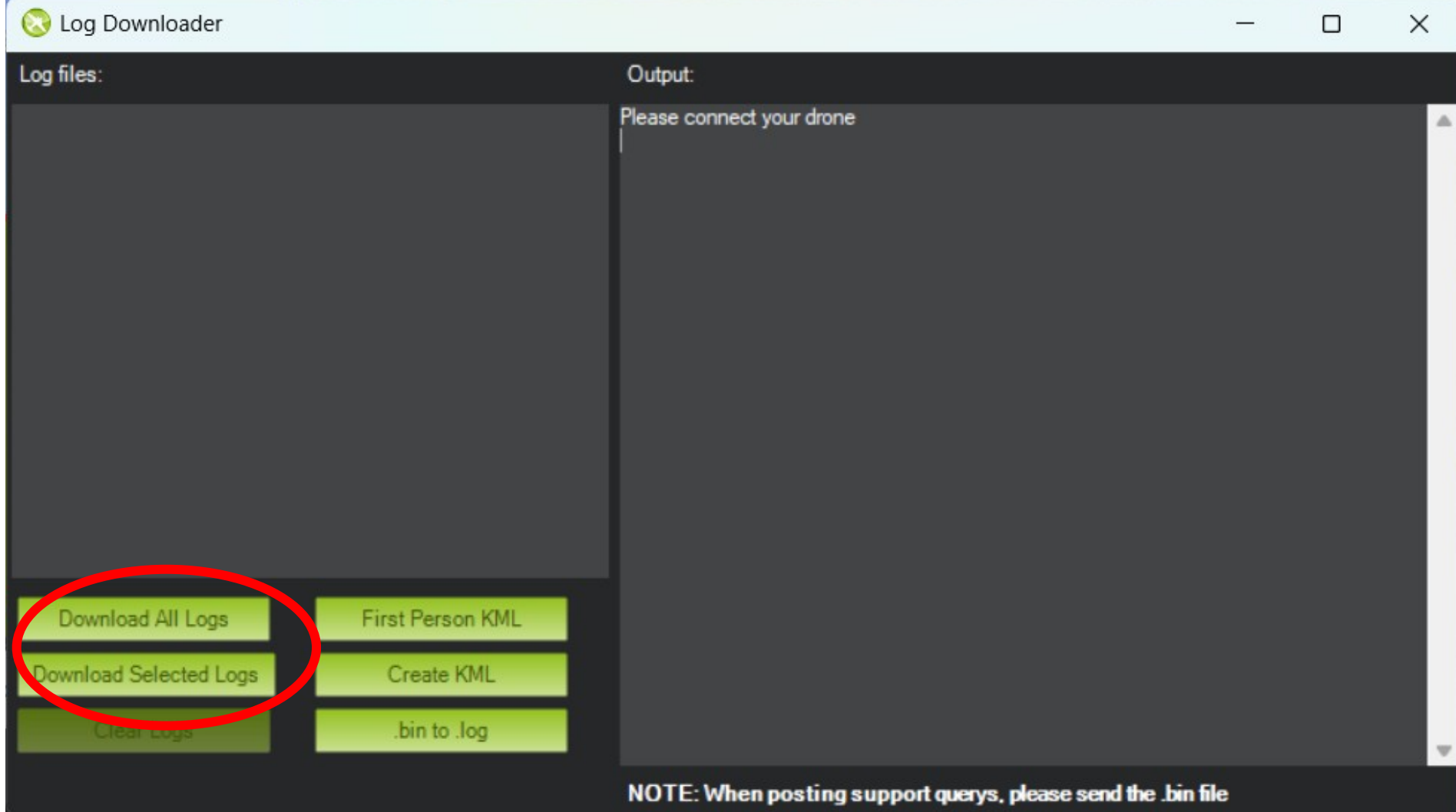
Transponder Status Servo/Relay Aux Function Scripts Payload Control Telemetry Logs **DataFlash Logs**

Download DataFlash Log Via Mavlink Review a Log Auto Analysis

Create KML + gpx Convert .Bin to .Log Create Matlab File

Geo Reference Images





ANALYZER

FILE

New Session Open Session Save Session **Import** Add Custom Signal Add Figure Attitude IMU Trajectory Delete Add Function Manage Function 2D Map 3D Map Data Cursor Export

Figures

From ULOG
Load .ulg file or .mat file with ulogreader object

From TLOG
Load .tlog file or .mat file with mavlinktlog object

From BIN
Load .bin file or .mat file with ardupilotreader object

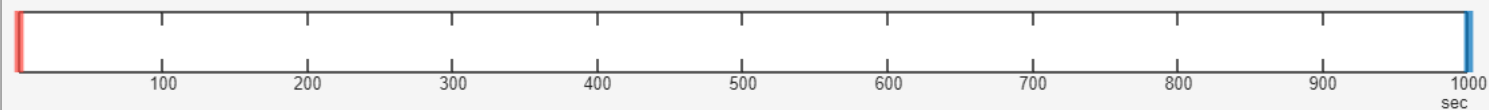
From Workspace
Load a ulogreader or mavlinktlog or ardupilotreader object, or custom log data and flightLogSignalMapping object from Workspace

Flight Modes

Flight mode data unavailable

Annotation

Panner



From (sec)

1



Reset Limits

To (sec)

1000

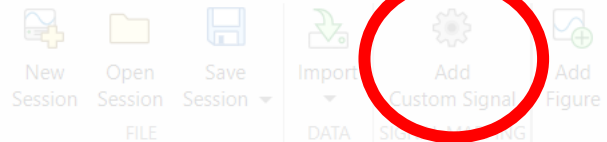
Details

Signals

Add Signal

Delete Signal

	Signal Name	X-Axis	Y-Axis
☐			



Start Time (sec)	End Time (sec)	Flight Mode
0.6410	0.6410	MANUAL

Add Custom Signal

Signal Name

Click on any signal in the available signals panel to expand the signal group. Select and add signals from one signal group to the signals preview list for custom mapping. You can specify the signal name, multiplier value, and units from the signal preview list.
To remove any added signal, click on the signal in the Signal Preview table and click the Remove Signals button.

Available Signals

☐ AOA
☒ ATT
☒ TimeUS
☒ DesRoll
☒ Roll
☒ DesPitch
☒ Pitch
☒ DesYaw
☒ Yaw
☒ ErrRP

Signal Preview

	Signal	Multiplier	Units
1	TimeUS	1	N/A
2	DesRoll	1	N/A
3	Roll	1	N/A
4	DesPitch	1	N/A
5	Pitch	1	N/A
6	DesYaw	1	N/A
7	Yaw	1	N/A
8	ErrRP	1	N/A

Add Signals

Remove Signals

OK

Cancel

Panner

0 2 4 6 8 10 12 14 16 $\times 10^{12}$ sec

From (sec)

0

Reset Limits

To (sec)

1.686e+13

ANALYZER

New Session Open Session Save Session Import Add Custom Signal

FILE DATA SIGNAL MAPPING

Figures

☒ Figure 1

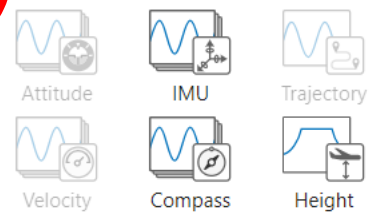
Flight Modes

Start Time (sec)	End Time (sec)	Flight Mode
0.6410	0.6410	MANUAL

Annotation

Add Figure

Plots



CUSTOM PLOTS



XY - Add blank plot for 2-D data the gallery to this figure

Delete Add Function Manage Function 2D Map 3D Map Data Cursor Export

ANNOTATE VIEW CURSORS EXPORT

Details

Figure name Figure 1

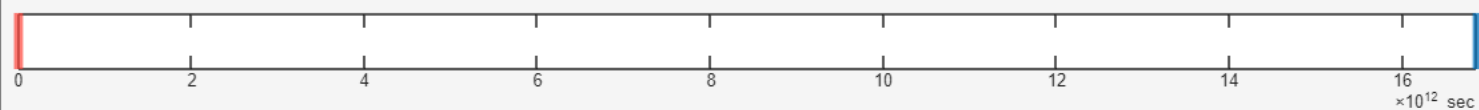
Signals

Add Signal

Delete Signal

Signal Name	X-Axis	Y-Axis

Panner



From (sec)

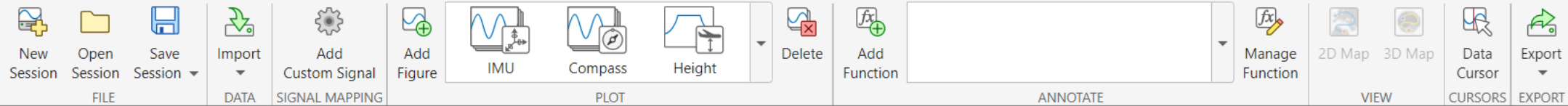
0

Reset Limits

To (sec)

1.686e+13

ANALYZER



Figures

Figure 1

☒ Custom XY

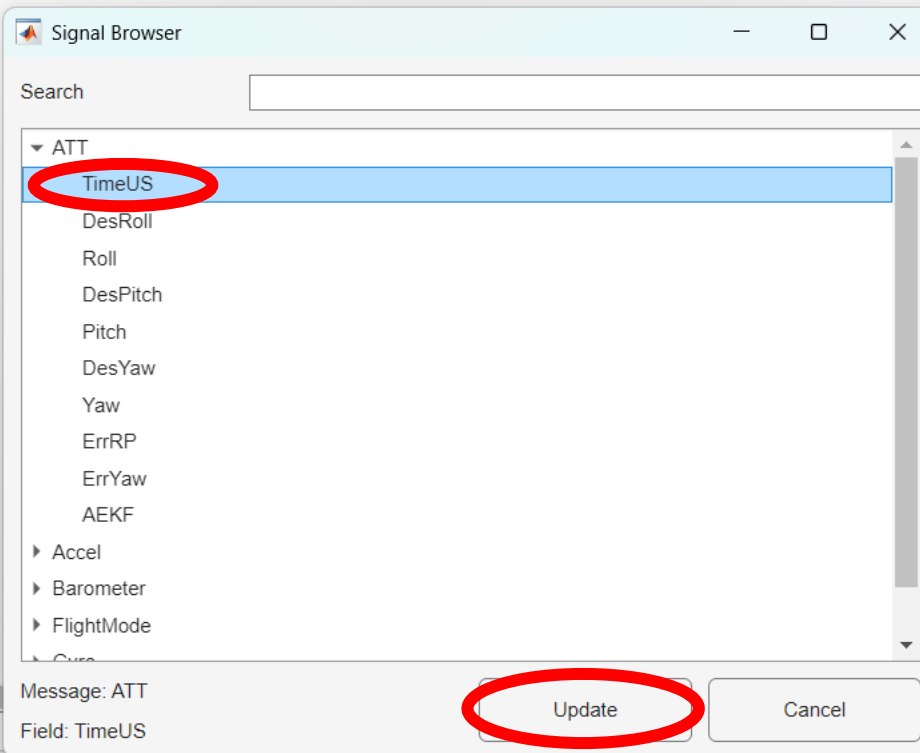
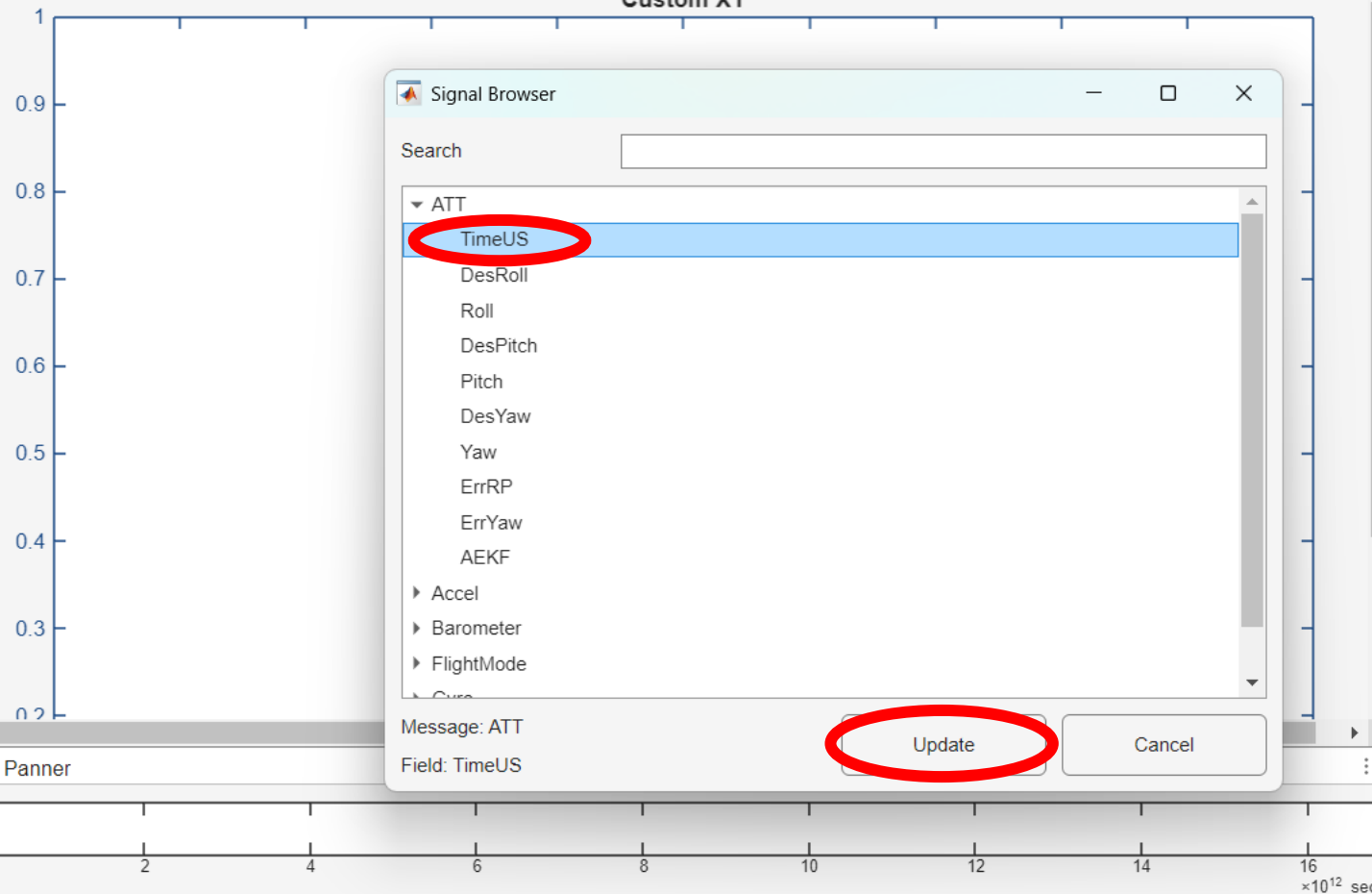
Flight Modes

Start Time (sec)	End Time (sec)	Flight Mode
0.6410	0.6410	MANUAL

Annotation

Figure 1

Custom XY



Details

Plot name Custom XY

☐ Axis Equal☐ Show Legend

Plot Type XY

Signals

Add Signal

Delete Signal

Signal Name	X-Axis	Y-Axis
☒ Line0	Double click to add signal	Double click to add signal

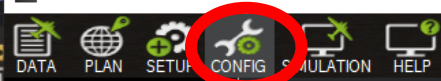
From (sec)

0

Reset Limits

To (sec)

1.686e+13



Flight Modes

Basic Tuning

Standard Params

Advanced Params

MAVftp

User Params

Full Parameter List

Full Parameter Tree

Planner

Command	Value	Units	Options	Desc	Fav
AHRS_TRIM_X	0	rad	-0.1745 +0.1745	Compensates for the roll angle difference between the control board and the frame. Positive values make the vehicle roll right.	☒
AHRS_TRIM_Y	0	rad	-0.1745 +0.1745	Compensates for the pitch angle difference between the control board and the frame. Positive values make the vehicle pitch up/back.	☒
BATT_AMP_OFFSET	0	V		Voltage offset at zero current on current sensor	☒
BATT_AMP_PERVLT	17	A/V		Number of amps that a 1V reading on the current sensor corresponds to. With a Pixhawk using the 3DR Power brick this should be set to 17. For the Pixhawk with the 3DR 4in1 ESC this should be 17.	☒
ACRO_TURN_RATE	180	deg/s	0 360	Acro mode turn rate maximum	☐
AHRS_COMP_BETA	0.1		0.001 0.5	This controls the time constant for the cross-over frequency used to fuse AHRS (airspeed and heading) and GPS data to estimate ground velocity. Time constant is 0.1/beta. A larger time constant will use GPS data less and a small time constant will use air data less.	☐
AHRS_CUSTOM_PIT	0	deg	-180 180	Autopilot mounting position pitch offset. Positive values = pitch up, negative values = pitch down. This parameter is only used when AHRS_ORIENTATION is set to CUSTOM.	☐
AHRS_CUSTOM_ROLL	0	deg	-180 180	Autopilot mounting position roll offset. Positive values = roll right, negative values = roll left. This parameter is only used when AHRS_ORIENTATION is set to CUSTOM.	☐
AHRS_CUSTOM_YAW	0	deg	-180 180	Autopilot mounting position yaw offset. Positive values = yaw right, negative values = yaw left. This parameter is only used when AHRS_ORIENTATION is set to CUSTOM.	☐
AHRS_EKF_TYPE	2		0:Disabled 2:Enable EKF2 3:Enable EKF3	This controls which NavEKF Kalman filter version is used for attitude and position estimation	☐
AHRS_GPS_GAIN	1		0.0 1.0	This controls how much to use the GPS to correct the attitude. This should never be set to zero for a plane as it would result in the plane losing control in turns. For a plane please use the default value of 1.0.	☐
AHRS_GPS_MINSATS	6		0 10	Minimum number of satellites visible to use GPS for velocity based corrections attitude correction. This defaults to 6, which is about the point at which the velocity numbers from a GPS become too unreliable for accurate correction of the accelerometers.	☐
AHRS_GPS_USE	1		0:Disabled 1:Enabled	This controls whether to use dead-reckoning or GPS based navigation. If set to 0 then the GPS won't be used for navigation, and only dead reckoning will be used. A value of zero should never be used for normal flight. Currently this affects only the DCM-based AHRS: the EKF uses GPS whenever it is available.	☐
AHRS_ORIENTATION	0		0:None 1:Yaw45 2:Yaw90 3:Yaw135 4:Yaw180 5:Yaw225 6:Yaw270 7:Yaw315 8:Roll180 9:Roll180Yaw45 10:Roll180Yaw90 11:Roll180Yaw135 12:Pitch180 13:Roll180Yaw225 14:Roll180Yaw270 15:Roll180Yaw315 16:Roll90 17:Roll90Yaw45 18:Roll90Yaw90 19:Roll90Yaw135 20:Roll270 21:Roll270Yaw45 22:Roll270Yaw90 23:Roll270Yaw135 24:Pitch90 25:Pitch270 26:Pitch180Yaw90 27:Pitch180Yaw270 28:Roll90Pitch90 29:Roll180Pitch90 30:Roll270Pitch90 31:Roll90Pitch180 32:Roll270Pitch180 33:Roll90Pitch270 34:Roll180Pitch270 35:Roll270Pitch270 36:Roll90Pitch180Yaw90 37:Roll90Yaw270 38:Yaw293Pitch68Roll180 39:Pitch315 40:Roll90Pitch315 100:Custom	Overall board orientation relative to the standard orientation for the board type. This rotates the IMU and compass readings to allow the board to be oriented in your vehicle at any 90 or 45 degree angle. This option takes affect on next boot. After changing you will need to re-level your vehicle.	☐
AHRS_RP_P	0.2		0.1 0.4	This controls how fast the accelerometers correct the attitude	☐
AHRS_TRIM_Z	0	rad	-0.1745 +0.1745	Not Used	☐
AHRS_WIND_MAX	0	m/s	0 127	This sets the maximum allowable difference between ground speed and airspeed. This allows the plane to cope with a failing airspeed sensor. A value of zero means to use the airspeed as is.	☐
AHRS_YAW_P	0.2		0.1 0.4	This controls the weight the compass or GPS has on the heading. A higher value means the heading will track the yaw source (GPS or compass) more rapidly.	☐
AHRS_YAW_OFFSET	0.0	deg	-0.0 0.0	Accelerometer error threshold used to determine inconsistent accelerometers. Compares this error range to other accelerometers to detect a hardware or calibration error. Lower value means tighter check and	☐

Load from file

Save to file

Write Params

Compare Params

All Units are in raw format with no scaling

3DR_Iris+_AC34

Load Presaved

Reset to Default

Search

Modified

