Skye2 Nano Quick Start Guide

The setup and configuration described in this chapter apply when using the Skye2 Nano with a controller running ArduPilot firmware.

Enable

Run Mission Planner and go to the Config > FULL Parameter List interface to set the following parameters and then restart the vehicle.

//If connected to CAN1

- CAN_P1_DRIVER=1

- CAN_D1_PROTOCOL=1

//If connected to CAN2

- CAN_P2_DRIVER=1

- CAN_D2_PROTOCOL=1

**//Set the airspeed sensor type to UAVCAN and enable it.**

- ARSPD_TYPE=8

- ARSPD_USE=1

Airspeed offset calibration

When there is no wind and the airspeed display is greater than 3m/s, please reset the airspeed to zero before taking off.

- Run the Mission planner software and connect the flight controller
- Make sure the pitot tube is in a windless environment
- Open Mission planner>Flight data>Action bar

- Select "Preflight Calibration" in the first check box; click the "Perform Action" button on the right
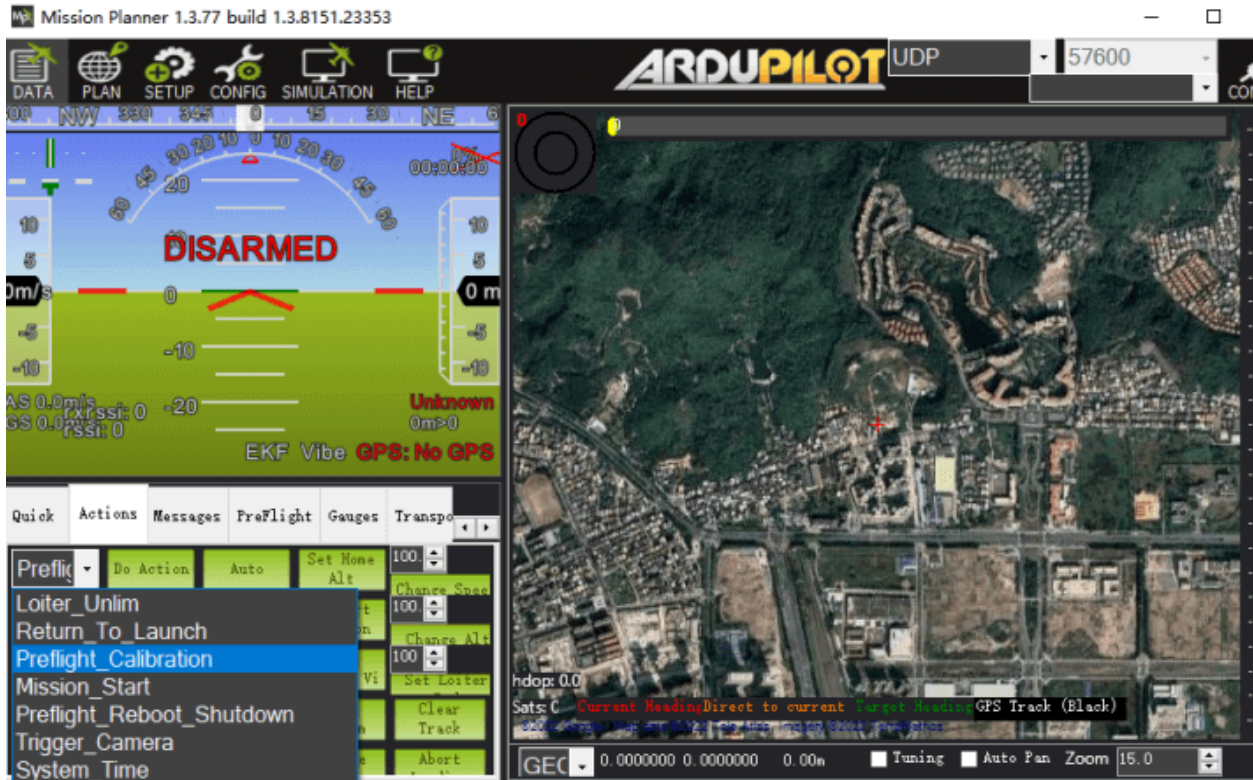
Pre-flight inspection

Before flying, please connect to the ground station to check that there is no wind and ensure that the airspeed value is within the range of 0~3m/s (if it exceeds the range, need perform airspeed offset calibration)

- Hold the pitot tube with your hand and blow air into the pitot tube. If the airspeed value changes according to the airflow speed, the inspection is complete.

Airspeed calibration

Note

The airspeed ratio of different installations and individual airspeed gauges will be somewhat different. The airspeed gauge needs to be calibrated on the first flight.

```
//Enable automatic airspeed calibration
- ARSPD_AUTOCAL=1
```

Perform calibration (choose one of the following two methods):
- **A:** Lift off in QStabilize or QLoiter multi-axis mode and convert to FBWA (self-stabilizing A mode) to control the drone to fly and hover for about 5 circles. After the ground station message bar prompts that the calibration is completed, execute the landing. After the calibration is completed Set ARSPD_AUTOCAL to 0.
- **B:** If you don't know how to fly in FBWA mode, you can fly with the airspeed sensor enabled but not using it (ARSPD_USE=1; ARSPD_TYPE=8; do not fly in a windy environment Perform this operation); the aircraft will fly using ground speed (relative ground speed), and use Loiter mode to hover for about 5 circles after takeoff. The ground station message bar prompts that after the calibration is completed, perform landing. After the calibration is completed, set ARSPD_AUTOCAL to 0.