

LeddarOne Acquisition Settings

Acquisition Settings ✕

Accumulation: 1024

Oversampling: 8

Measurement Rate: 8.8 Hz

Points: 15

Approximate Range: 41.8m

Smoothing: 0 Disabled

LED Control

Manual Control

Led Intensity: 100

Automatic Control

Change Delay: 1 (114 ms)

LeddarOne Communication Settings

Communication Settings ✕

Baud Rate: 115200

Modbus Address: 1

LeddarOne Device State

Device State ✕

Temperature Device: 30.8 C	Timers & Load 0 00:02:20 Measurement Rate: 8.97 Hz
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Automatic Parameter Values

LED Intensity: 100 %

Device Information

Serial Number: EH03133

Version: FPGA: 1.1 Software: 6 () CRC: 0

Part Numbers: Hardware: 75B0017-2 Software: 53A0025-3

Ardupilot SERIAL4 parameter

Mission Planner 1.3.41 build 1.1.6110.31287 APM:Copter V3.4.3-rc1 (6b923a03)

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Command	Value	Units	Options	Desc
SERIAL2_BAUD	57		1:1200 2:2400 4:4800 9:3600 19:19200 38:38400 57:57600 111:111100 115:115200 500:500000 921:921600 1500:1500000	The baud rate of the Telem2 port. The APM2 can support all baudrates up to 115, and rates of up to 1500. If you setup a rate you cannot support on APM2 and then can't load a firmware from a different vehicle type. That will reset all your parameters to defaults.
SERIAL2_PROTOCOL	1		1:GCS Mavlink 3:Frsky D-POR 4:Frsky S-POR 5:GPS 7:Alexmos Gimbal Serial 8:S ToRM32 Gimbal Serial 9:Lidar	Control what protocol to use on the Telem2 port. Note that the Frsky options require a wiki for details.
SERIAL3_BAUD	38		1:1200 2:2400 4:4800 9:3600 19:19200 38:38400 57:57600 111:111100 115:115200 500:500000 921:921600 1500:1500000	The baud rate used for the Serial 3 (GPS). The APM2 can support all baudrates up to support rates of up to 1500. If you setup a rate you cannot support on APM2 and then can't load a firmware from a different vehicle type. That will reset all your parameters to de
SERIAL3_PROTOCOL	5		1:GCS Mavlink 3:Frsky D-POR 4:Frsky S-POR 5:GPS 7:Alexmos Gimbal Serial 8:S ToRM32 Gimbal Serial 9:Lidar	Control what protocol Serial 3 (GPS) should be used for. Note that the Frsky option the wiki for details.
SERIAL4_BAUD	115		1:1200 2:2400 4:4800 9:3600 19:19200 38:38400 57:57600 111:111100 115:115200 500:500000 921:921600 1500:1500000	The baud rate used for Serial4. The APM2 can support all baudrates up to 115, and rates of up to 1500. If you setup a rate you cannot support on APM2 and then can't firmware from a different vehicle type. That will reset all your parameters to defaults.
SERIAL4_PROTOCOL	9		1:GCS Mavlink 3:Frsky D-POR 4:Frsky S-POR 5:GPS 7:Alexmos Gimbal Serial 8:S ToRM32 Gimbal Serial 9:Lidar	Control what protocol Serial4 port should be used for. Note that the Frsky options require a wiki for details.
SERIAL5_BAUD	57			
SERIAL5_PROTOCOL	-1			
SIMPLE	0			Bitmask which holds which flight modes use simple heading mode (eg bit 0 = 1 means
SPRAY_ENABLE	0		0:Disabled 1:Enabled	Allows you to enable (1) or disable (0) the sprayer
SR0_ADSB	5			
SR0_EXT_STAT	2			
SR0_EXTRAI	4			
SR0_EXTRAI2	4			
SR0_EXTRAI3	2			
SR0_PARAMS	10			
SR0_POSITION	2			
SR0_RAW_CTRL	2			
SR0_RAW_SENS	2			
SR0_RC_CHAN	2			
SR1_ADSB	5			

Ardupilot RNFND paramter

Mp Mission Planner 1.3.41 build 1.1.6110.31287 APM:Copter V3.4.3-rc1 (6b923a03)

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Command	Value	Units	Options	Desc
RNGFND_ADDR	0		0:1:27	This sets the bus address of the sensor, where applicable. Used for the LightWare different addresses. A value of 0 disables the sensor.
RNGFND_FUNCTION	0		0:Linear 1:Inverted 2:Hyperbolic	Control over what function is used to calculate distance. For a linear function, the inverted function the distance is (offset-voltage)*scaling. For a hyperbolic function the distance is (offset-voltage)*scaling. For a hyperbolic function the distance is in meters.
RNGFND_GAIN	0.8		0.01 2.0	Used to adjust the speed with which the target altitude is changed when objects
RNGFND_GNDCLEAR	20	centimeter	0:1:27	This parameter sets the expected range measurement (in cm) that the range find
RNGFND_MAX_CM	4000	centimeter		Maximum distance in centimeters that range finder can reliably read
RNGFND_MIN_CM	5	centimeter		Minimum distance in centimeters that range finder can reliably read
RNGFND_OFFSET	0	volts		Offset in volts for zero distance for analog rangefinders. Offset added to distance
RNGFND_PIN	-1		-1:Not Used 0:APM2-A0 1:APM2-A1 2:APM2-A2 3:APM2-A3 4:APM2-A4 5:APM2-A5 6:APM2-A6 7:APM2-A7 8:APM2-A8 9:APM2-A9 11:PX4-airspeed port 15:Pixhawk-airspeed port 64:APM1-airspeed port	Analog pin that rangefinder is connected to. Set this to 0.8 for the APM2 analog 'airspeed' port on the end of the board. Set to 11 on PX4 for the analog 'airspeed' port.
RNGFND_P_WRRING	0	meters	0:32767	This parameter sets the estimated terrain distance in meters above which the se
RNGFND_RMETRIC	1		0:No 1:Yes	This parameter sets whether an analog range finder is ratiometric. Most analog ran
RNGFND_SCALING	1	meters/Vol		Scaling factor between rangefinder reading and distance. For the linear and invert
RNGFND_SETTLE	0	milliseconds		The time in milliseconds that the rangefinder reading takes to settle. This is only
RNGFND_STOP_PIN	-1		-1:Not Used 50:Pixhawk AUXOUT1 51:Pixhawk AUXOUT2 52:Pixhawk AUXOUT3 53:Pixhawk AUXOUT4 54:Pixhawk AUXOUT5 55:Pixhawk AUXOUT6 111:PX4 FMU Relay1 112:PX4 FMU Relay2 113:PX4IO Relay1 114:PX4IO Relay2 115:PX4IO ACC1 116:PX4IO ACC2	Digital pin that enables/disables range finder measurement for an analog range find
RNGFND_TYPE	12		0:None 1:Analog 2:APM2-MaxbotixI2C 3:APM2-PulsedLightI2C 4:PX4-I2C 5:PX4-PWM 6:BBB-PRU 7:LightWareI2C 8:LightWareSerial	What type of rangefinder device that is connected
RNGFND2_ADDR	0		0:1:27	This sets the bus address of the sensor, where applicable. Used for the LightWare
RNGFND2_FUNCTION	0		0:Linear 1:Inverted 2:Hyperbolic	Control over what function is used to calculate distance. For a linear function, th
RNGFND2_GNDCLEAR	10	centimeter	0:1:27	This parameter sets the expected range measurement (in cm) that the second ra