



FLYWOO LR4 EXPLORER QUAD ANALOG User Manual

[Home](#) » [FLYWOO](#) » FLYWOO LR4 EXPLORER QUAD ANALOG User Manual 

Contents

- [1 FLYWOO LR4 EXPLORER QUAD ANALOG](#)
- [2 drone introduction](#)
- [3 Configuration and wiring diagram description](#)
- [4 Receiver binding](#)
 - [4.1 GPS rescue mode](#)
- [5 Bluetooth function](#)
- [6 Documents / Resources](#)
 - [6.1 References](#)
- [7 Related Posts](#)

FLYWOO LR4 EXPLORER QUAD ANALOG



drone introduction

Explorer LR quad is the masterpiece of the collaboration between Flywoo and #micro long range original creator Dave_C . #Micro long range is a brand new field, and we will explore more fun in this field with Dave_C in the future.



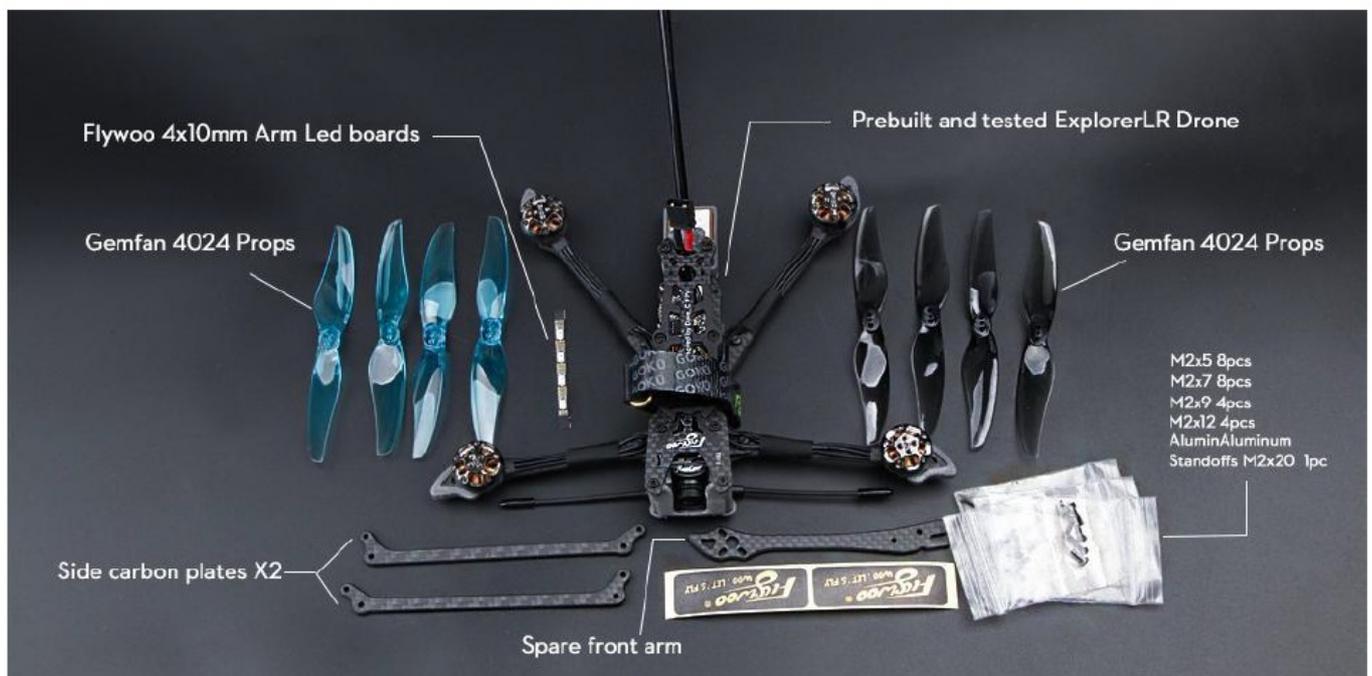
For me personally, Long Range cruising through epic landscapes is the best thing about FPV! But unfortunately, it

was always kind of difficult to practice legally and without bothering people with all the noise a massive 6 or 7" long-range quad produces.

So the basic idea behind the original Project #MicroLongRange was born: Scale down a 7" long-range quad until it is below 250g take-off weight. With the support of an awesome community on Facebook and Instagram as well as a massive development effort by Flywoo, this concept has seen a lot of improvements that are now all implemented in the Explorer LR!

This tiny quad is equipped with GPS, Crossfire, and an independent model finder to give you the necessary confidence to push it to the maximum range of digital and analog video transmission. The powertrain with its GOKU 16x16 stack and the all-new 2750kV 1404 motors spinning 4" props is optimized for maximum efficiency and low weight: Flight times of way over ten minutes on a regular 850mah 4S LiPo battery are easily achievable! Cruising speeds of 40-50 kph (25-30mph) are astonishingly high for such a small quad and have allowed me to do 10km (6 miles) round trips easily. And the best thing about it: It's incredibly quiet! You will barely be able to hear it flying by as soon as you are a few dozen meters away. "

Configuration and wiring diagram description



Explorer LR 4 Vista / Nebula pro BNF Specification :

Goku F411 V2.1 nano stack 16x16
Dave_C & Nin 1404 V2 2750kv motors
Goku M8N mini gps v2.0
Flywoo Finder v1.0
Gemfan 4024 props
Atomic 5.8 G antenna RHCP
Camera: CADDX ANT
VTX: FLYWOO HM600

Recommend Battery :

Naked Gopro & SMO 4K & Insta360 go
—Explorer 18650/ Tattu 1050 4s mah — 650 4s mah

Highlights & Specification :

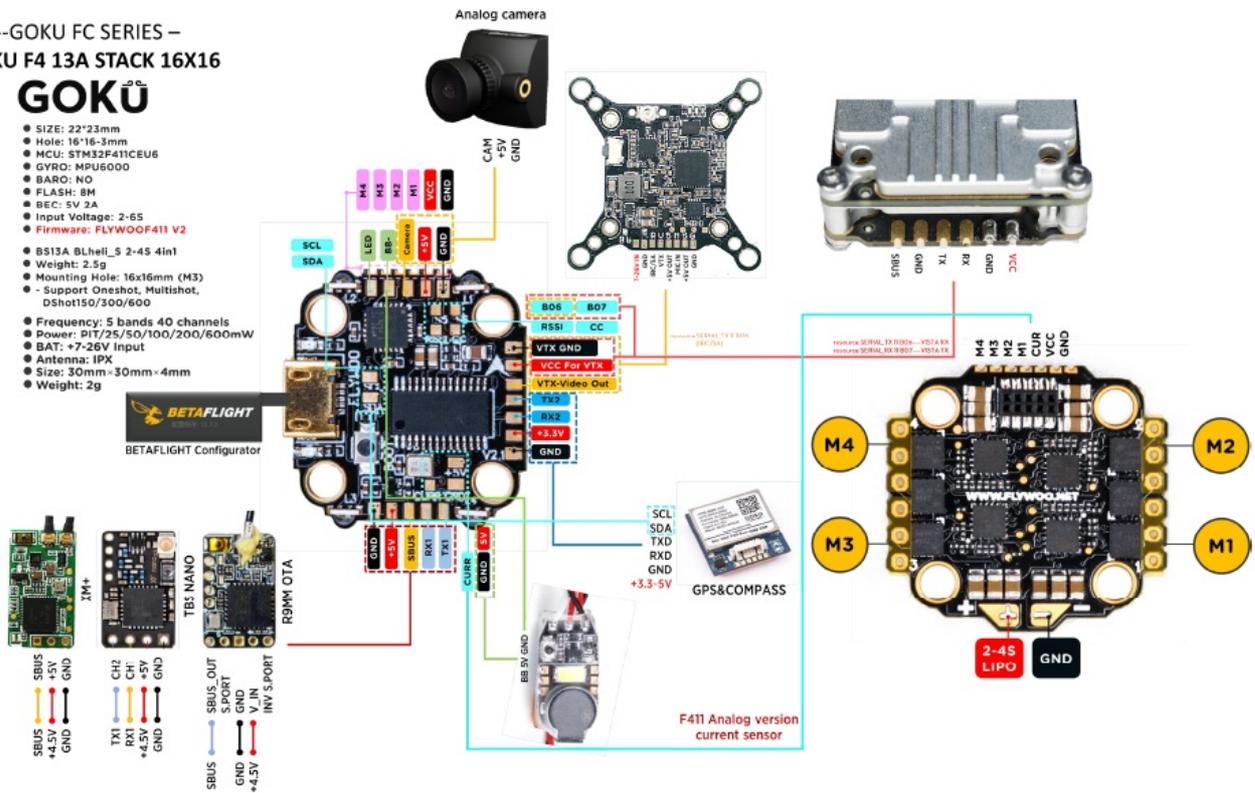
The lightweight 4-inch quad below 250g even if you connect with the battery, meet the current requested of FAA rules. Easy to control and long flight time, we strongly recommend to FPV beginners and pilots who like to cruise!

Equipped with GOKU 16X16 MICRO STACK, and NIN 1404 v2-2750kv, support 4s battery. You can get up to 20 minutes cruising! So this is a quad that is very suitable for FPV beginners and long-range enthusiasts! It is recommended installing side carbon fiber plate to increase the strength and stability of the Arm.

--GOKU FC SERIES --
GOKU F4 13A STACK 16X16

GOKU

- SIZE: 22*23mm
- Hole: 16*16-3mm
- MCU: STM32F411CEU6
- SYRD: MPU6000
- BARO: NO
- FLASH: 8M
- BEC: 5V 2A
- Input Voltage: 2-6S
- Firmware: **FLYWOODF411 V2**
- B513A BLHelix_S 2-4S 4in1
- Weight: 2.5g
- Mounting Hole: 16x16mm (M3)
- Support Oneshot, Multishot, DShot150/300/600
- Frequency: 5 bands 40 channels
- Power: PIT/25/50/100/200/600mW
- BAT: +7-28V input
- Antenna: 1PX
- Size: 30mm*30mm*4mm
- Weight: 2g

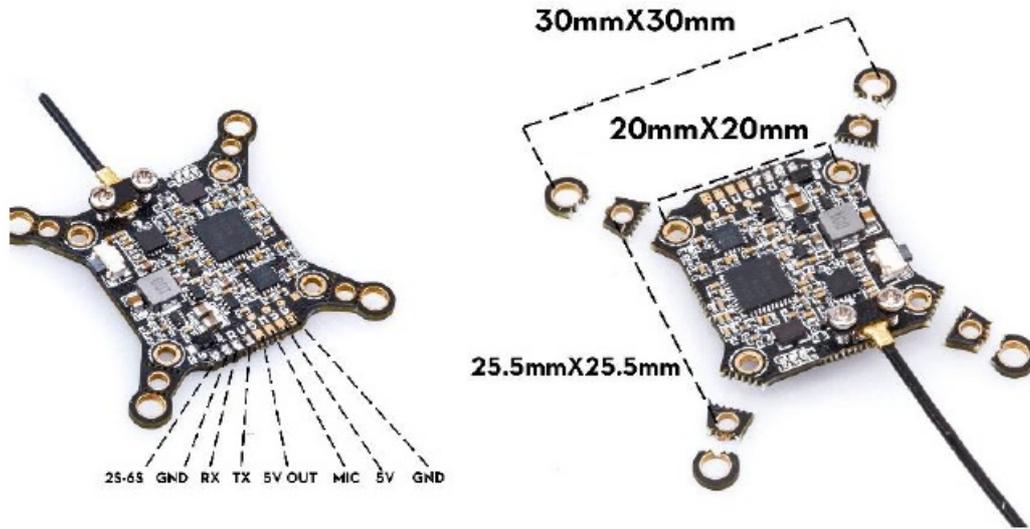


Identifier	Configuration/MSP	Serial Rx	Telemetry Output	Sensor Input	Peripherals
USB VCP	<input checked="" type="checkbox"/> 115200	<input type="checkbox"/>	Disabled AUTO	Disabled AUTO	Disabled AUTO
UART1	<input type="checkbox"/> 115200	<input checked="" type="checkbox"/>	Disabled AUTO	Disabled AUTO	Disabled AUTO
UART2	<input type="checkbox"/> 115200	<input type="checkbox"/>	Disabled AUTO	GPS 9600	Disabled AUTO
SOFTSERIAL1	<input type="checkbox"/> 115200	<input type="checkbox"/>	Disabled AUTO	Disabled AUTO	VTX (IRC Tran AUTO

RX IN (SBUS/CRSF)
GPS Serial Port
VTX IRC/SA

SOFTSERIAL1 TX is mapped to PIN B06
CLI: RESOURCE SERIAL_TX 11 B06

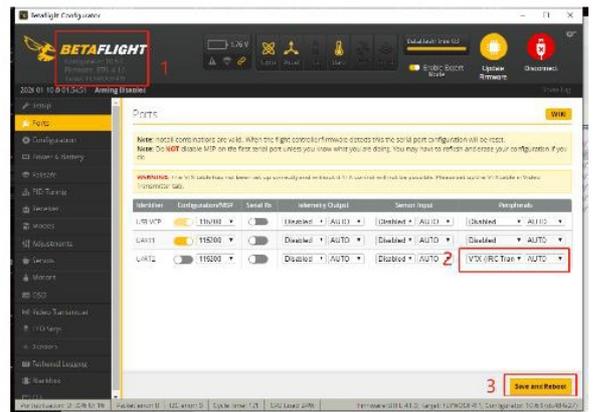
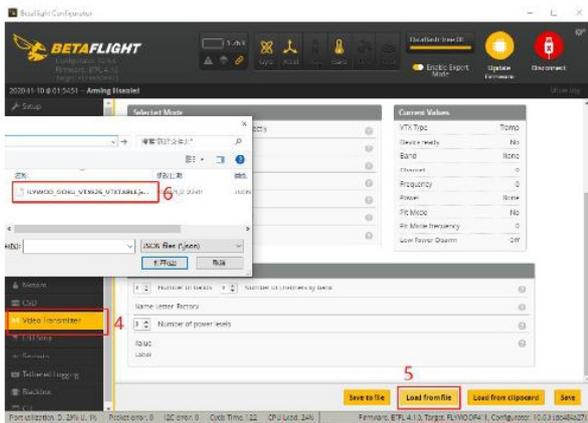
UART1: TBS/R9M/XM+/DSMX/SBUS receiver
UART2: GPS module, the default baud rate is 9600
SOFTSERIAL1: VTX IRC/SA Control

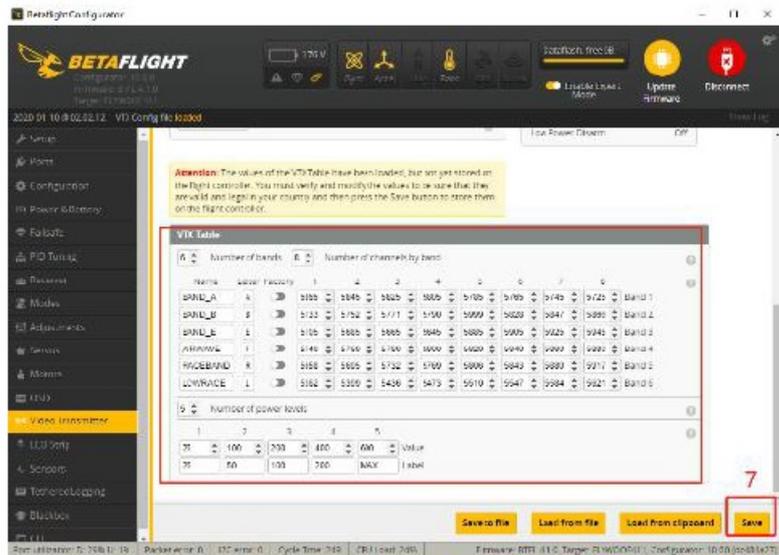


Frequency table :

FR/CH	CH1	CH2	CH3	CH4	CH5	CH6	CH7	CH8
A	5865	5845	5825	5805	5785	5765	5745	5725
b	5733	5752	5771	5790	5809	5828	5847	5866
E	5705	5685	5665	5645	5885	5905	5925	5945
F	5740	5760	5780	5800	5820	5840	5860	5880
r	5658	5695	5732	5769	5806	5843	5880	5917

<https://flywoo.net/pages/manual>





Receiver binding

TBS NANO 915:

When the USB is connected, the green light of the receiver flashes, and then bind according to the picture operation.

https://www.youtube.com/watch?v=iNKVcOLITM&ab_channel=Danimal3D



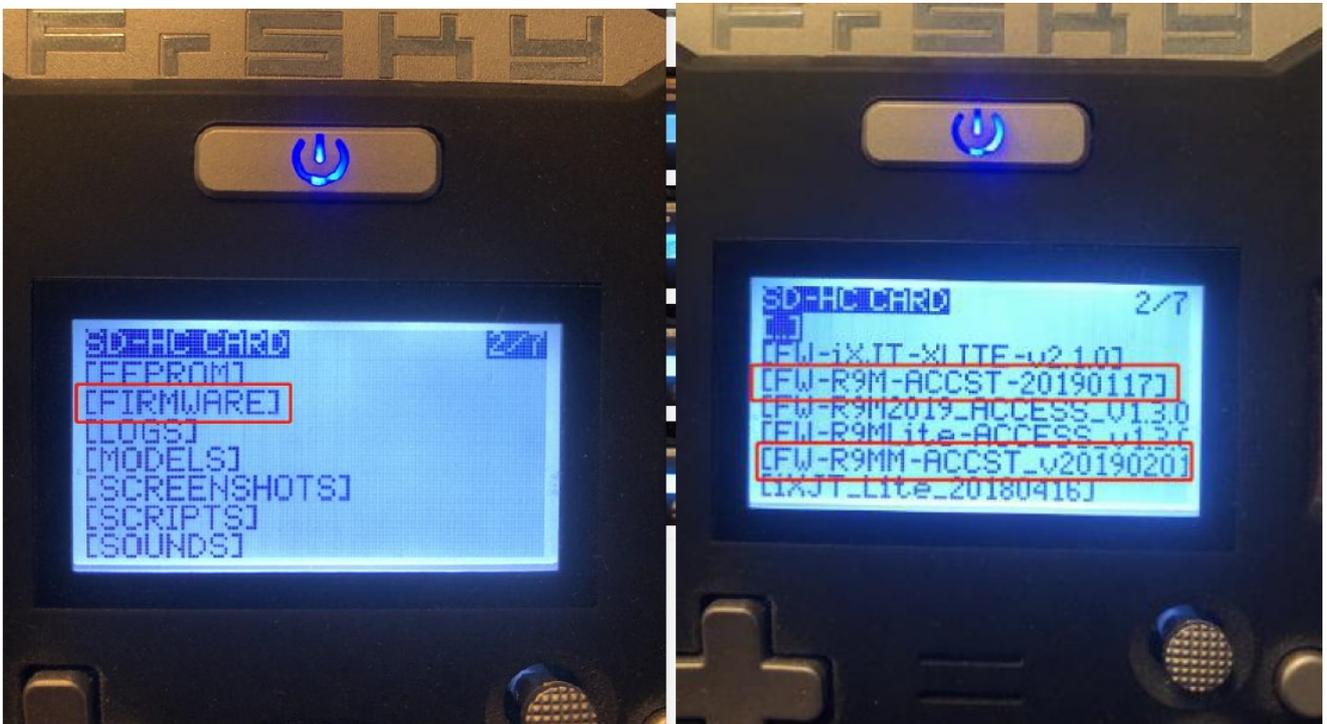
R9MM FCC ACCESS OTA

Make sure your remote control supports ACCESS protocol, then follow the link to register and bind

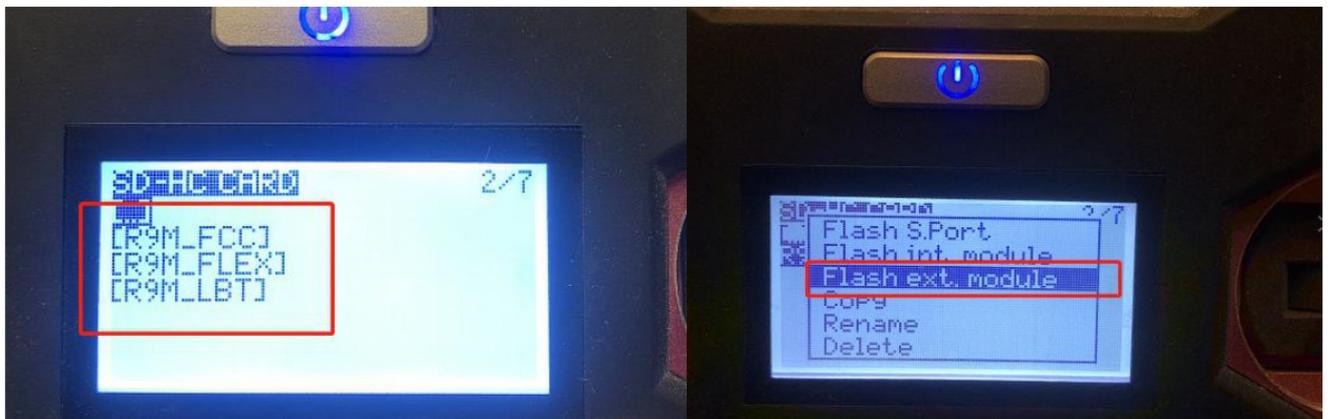
https://www.youtube.com/watch?v=az5hDdNBcjg&t=9s&ab_channel=FrSkyRC

If the remote control is ACCST protocol, please bind as follows:

- Put these two files into the firmware directory of the SD card of the remote control. R9MM firmware: FW-R9MM-ACCST_v20190201
R9M TX module: FW-R9M-ACCST-20190117



2. Insert the R9M TX module and write the firmware you need



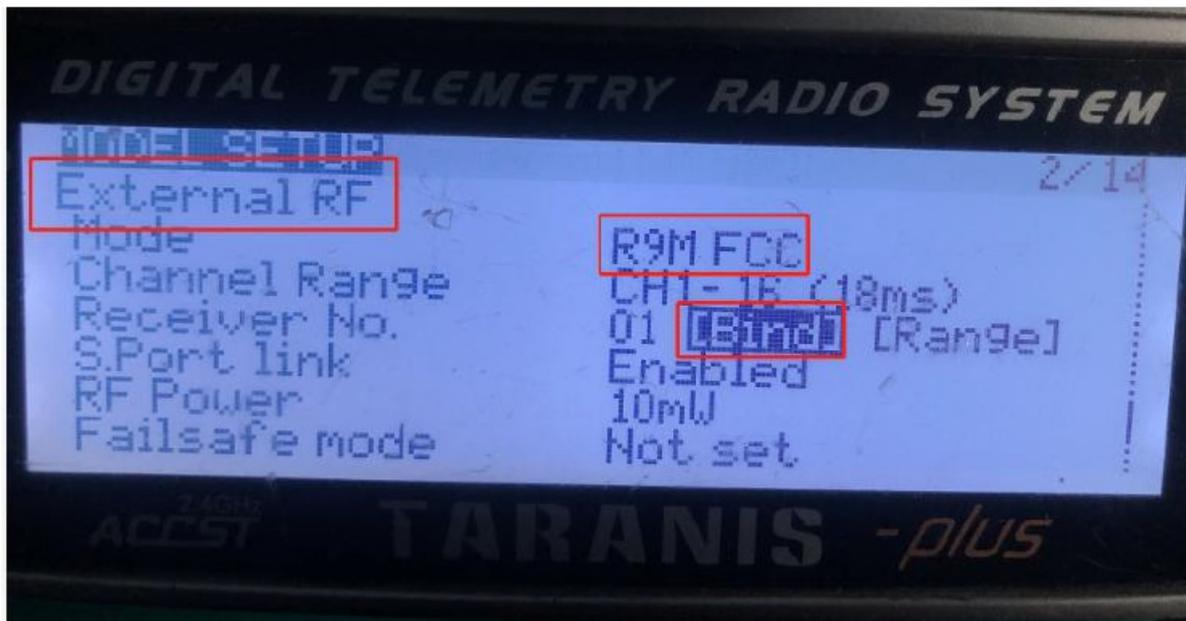
3. To write the firmware of the R9MM receiver, you need to remove the R9MM receiver, and then write the firmware by connecting to the S.PORT port.



4. After both R9M TX and R9MM RX are written into the ACCST firmware.

Binding method:

1. Press and hold the button of RX, power on, the red and green lights are always on.
2. Then after R9MM selects binding, RX red light flashes, and then exit
3. RX is powered on again, and only a green light is displayed, indicating that the binding is successful.

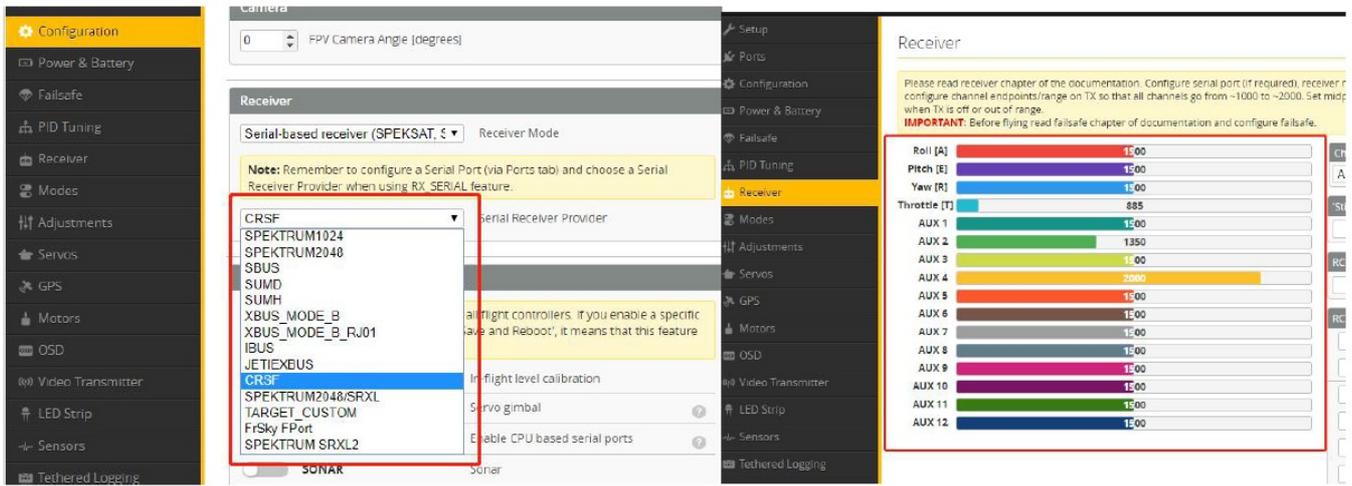


XM+ receiver:

1. Press the XM+ receiver button, USB power supply, the red and green lights are always on
2. The remote control turns on the binding mode, the green light flashes to indicate successful binding, turn off and restart

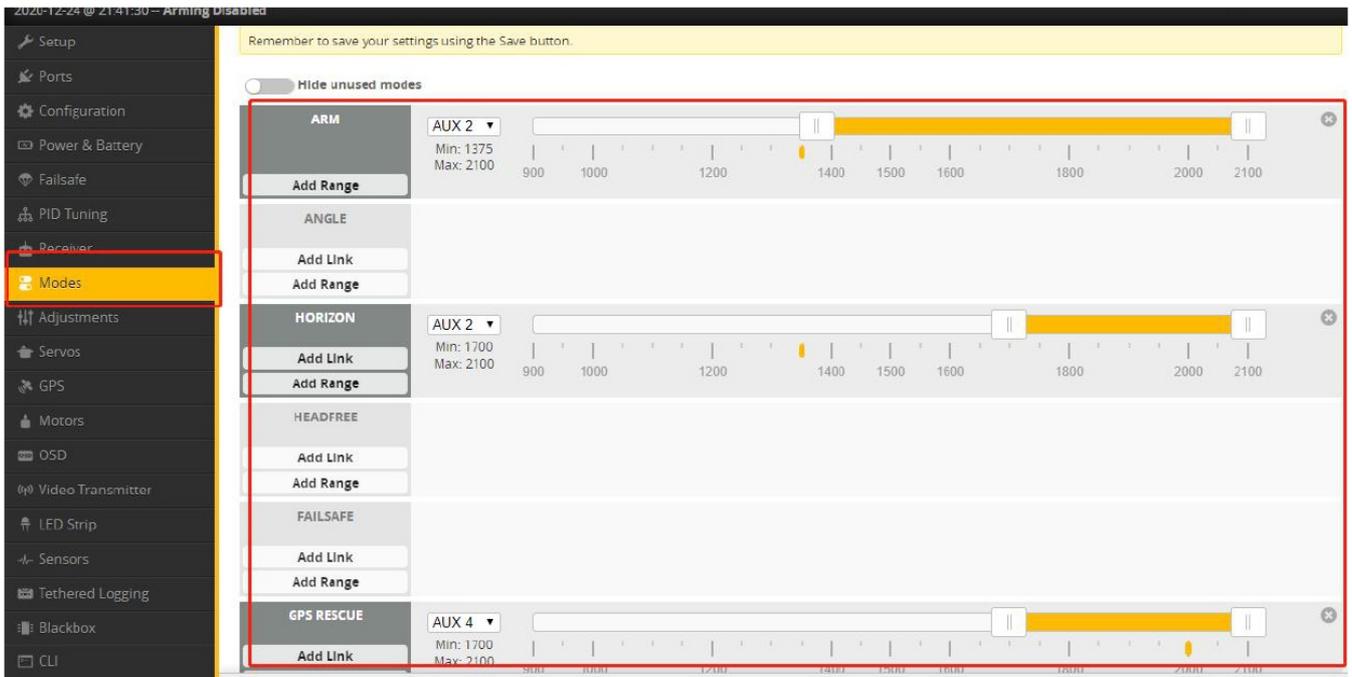


1. Then set the corresponding serial port and receiver protocol to ensure the normal output of each channel of the receiver.



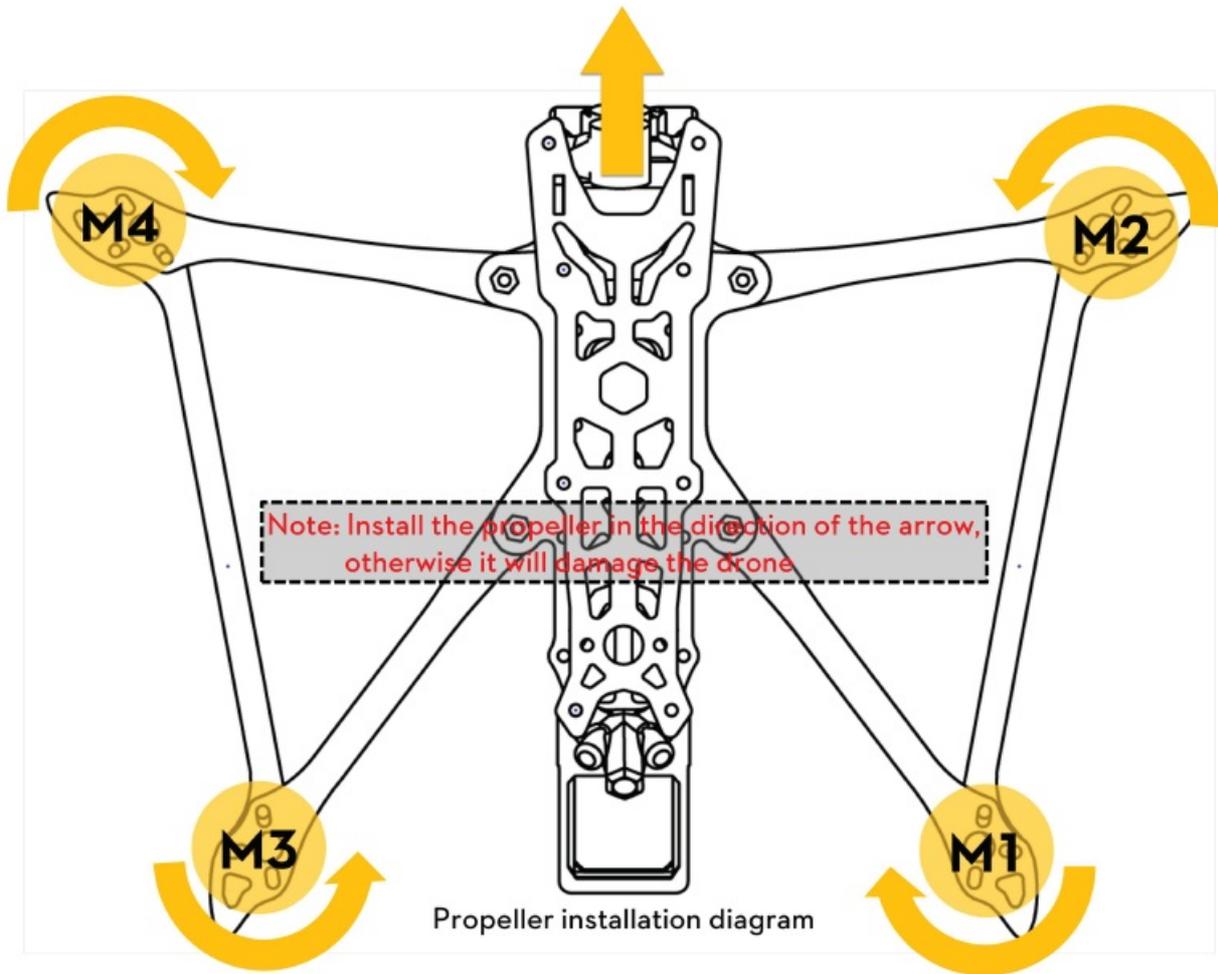
Mode setting

Set the ARM switch and flight mode switch, AUX* corresponds to the remote control switch, and the yellow area mark is turned on.



Motor test:

Unload the propeller, test the rotation direction of the motor, turn on the safety switch, and test the rotation of the motors one by one.



Motors

Voltage: 1.71 V Amperage: 0.00 A Amp. drawn: 0 mAh

Motors

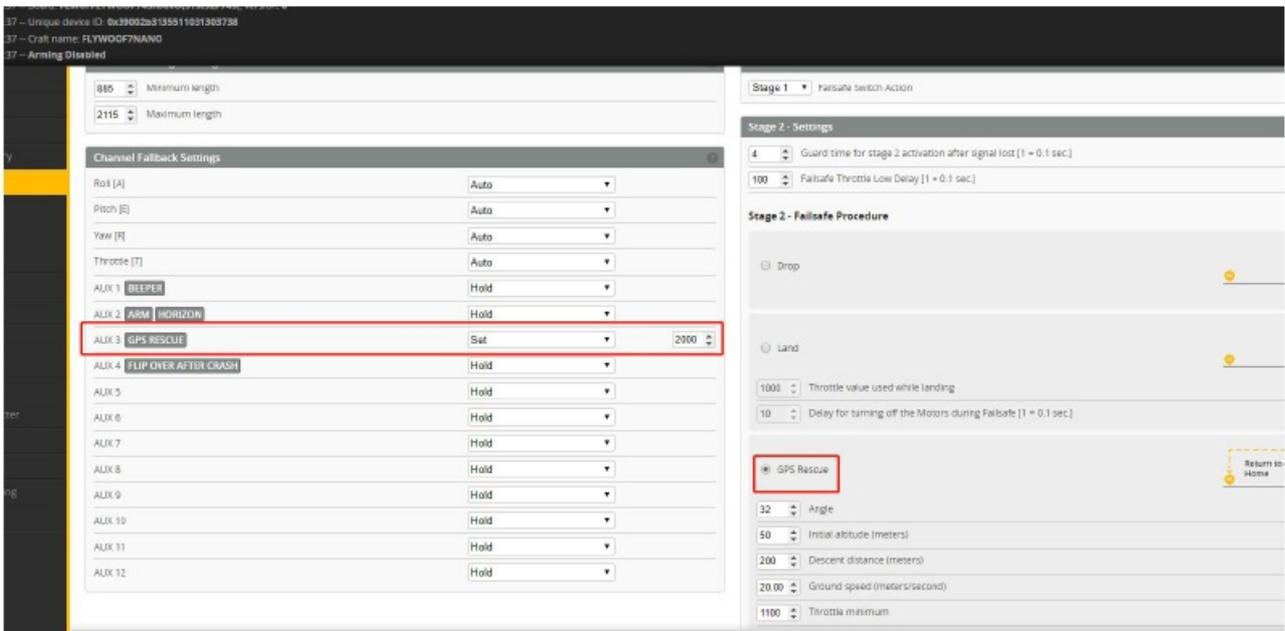
1	2	3	4	5	6	7	8
1088	1088	1088	1088	0	0	0	0
1089	1089	1089	1089	1000	1000	1000	1000

Motor Test: Moving the motors to 5. In order to prevent damage to the drone, enabling motor test will prevent the drone from flying. Enabling motor test will prevent the drone from flying. Motor test

GPS rescue mode

1. When GPS finds 5 satellites and locks, it will display latitude/longitude/altitude/distance information.

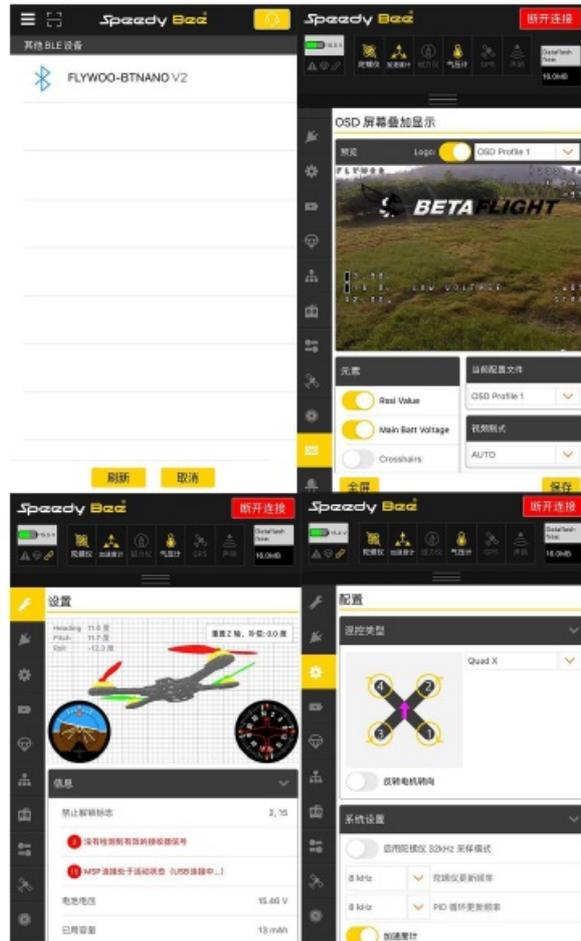
- GPS rescue can only be turned on when the flight distance data exceeds 100 meters, otherwise it will fail directly.
- After the GPS rescue is turned on, DRONE will turn around and rise gradually and return to the home location.
- DRONE will not automatically land. When the control is restored, you need to control DRONE to land.



Bluetooth function



Betaflight APP



Finder BUZZER function



The buzzer has two modes of operation:

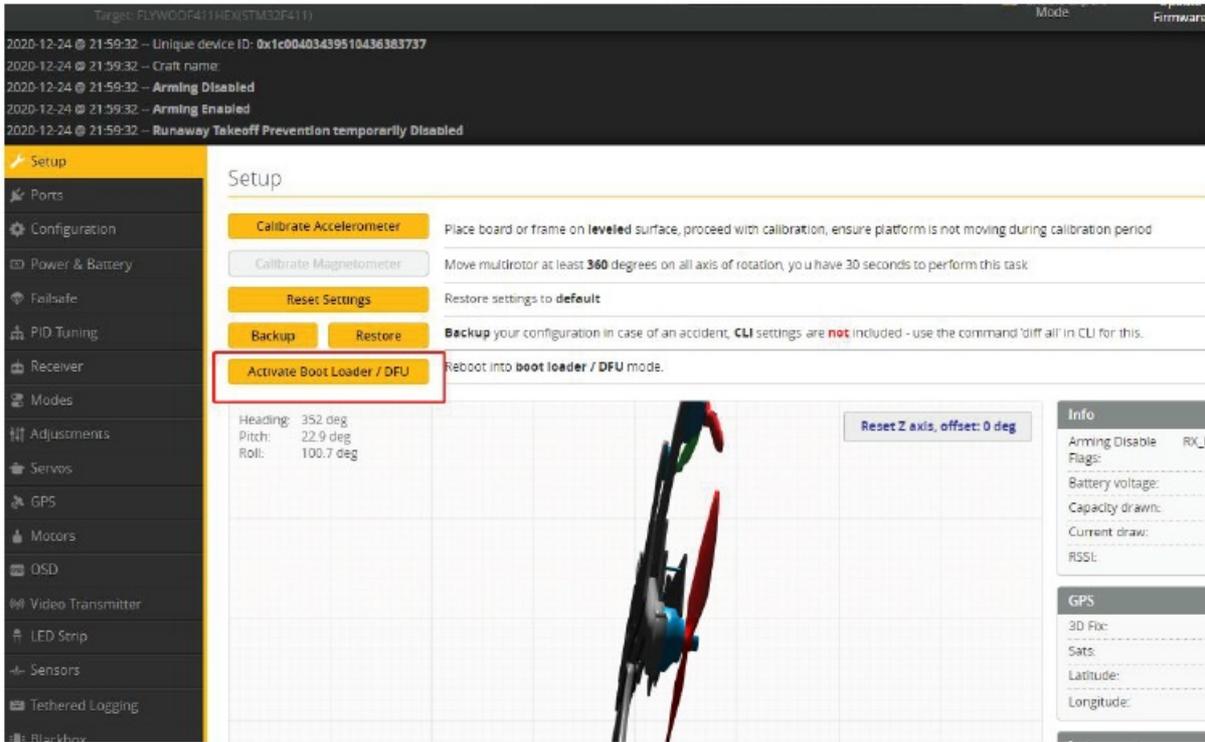
The buzzer has two modes of operation:

1. It is compatible with the functions of the traditional active buzzer and synchronized with the flight control.
2. When the flight control is normally connected, if the main battery in the flight is powered off, it can still automatically emit 100 dB of drip sound after 30 seconds of power failure, and the LED will emit white light.

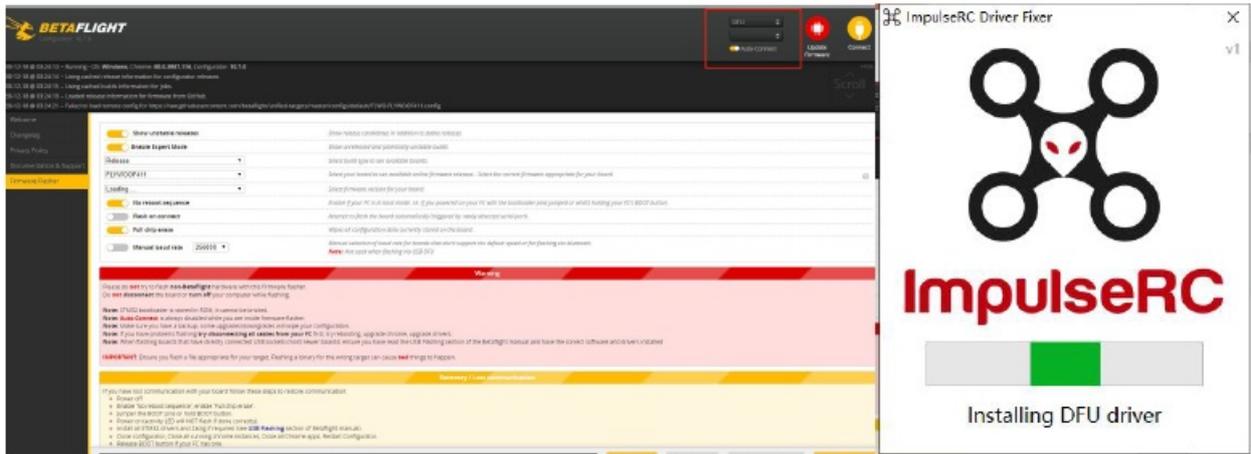
To turn off the buzzer: Press and hold the release button for more than 2 seconds, the Finder V1.0 turns off the sound.

Flight firmware upgrade and write default CLI

1. Activate DFU mode



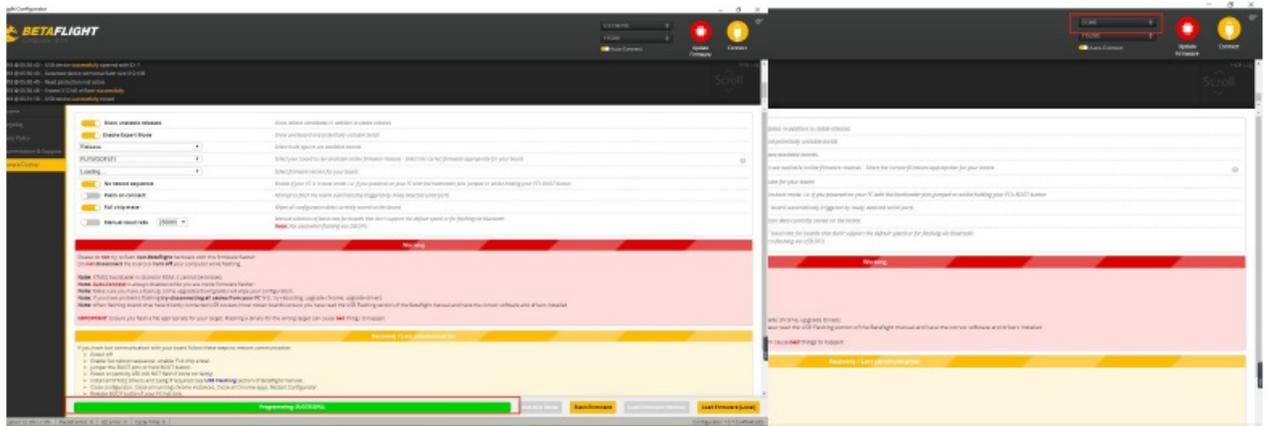
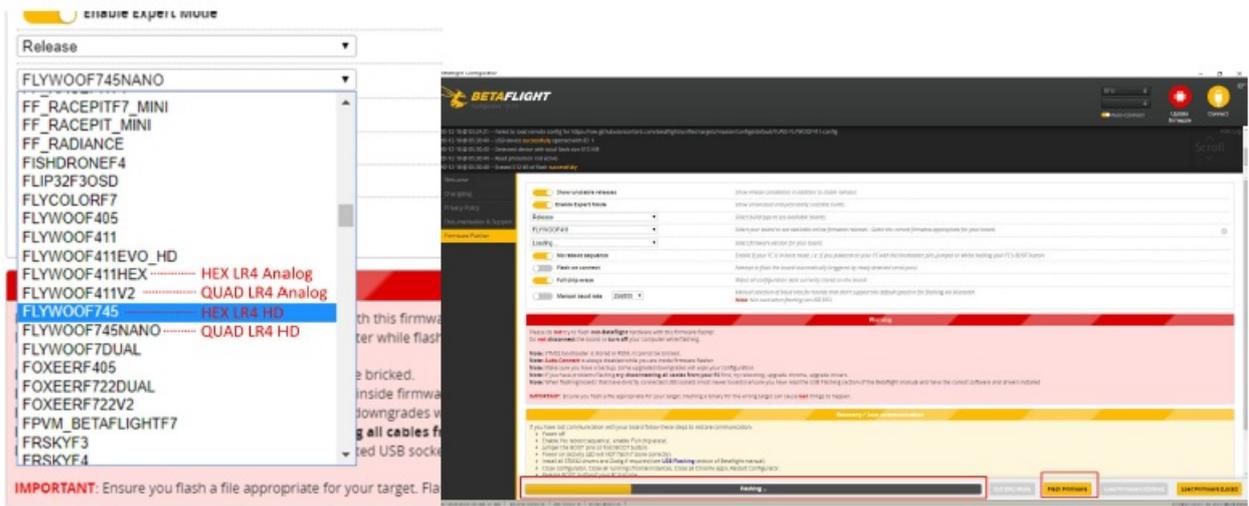
2. BF Configurator will display to enter DFU mode. If it does not enter DFU mode, it may be that the driver is not installed. The driver can be installed using IMPULSE RC software



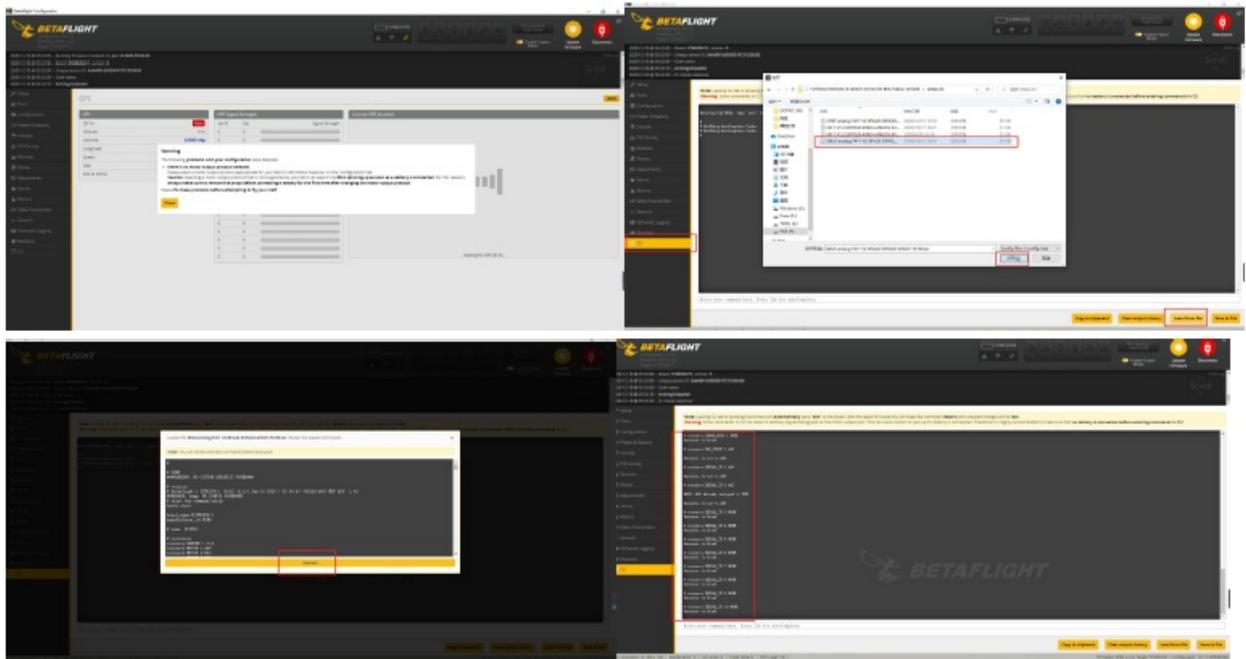
Driver software:

https://impulserc.blob.core.windows.net/utilities/ImpulseRC_Driver_Fixer.exe

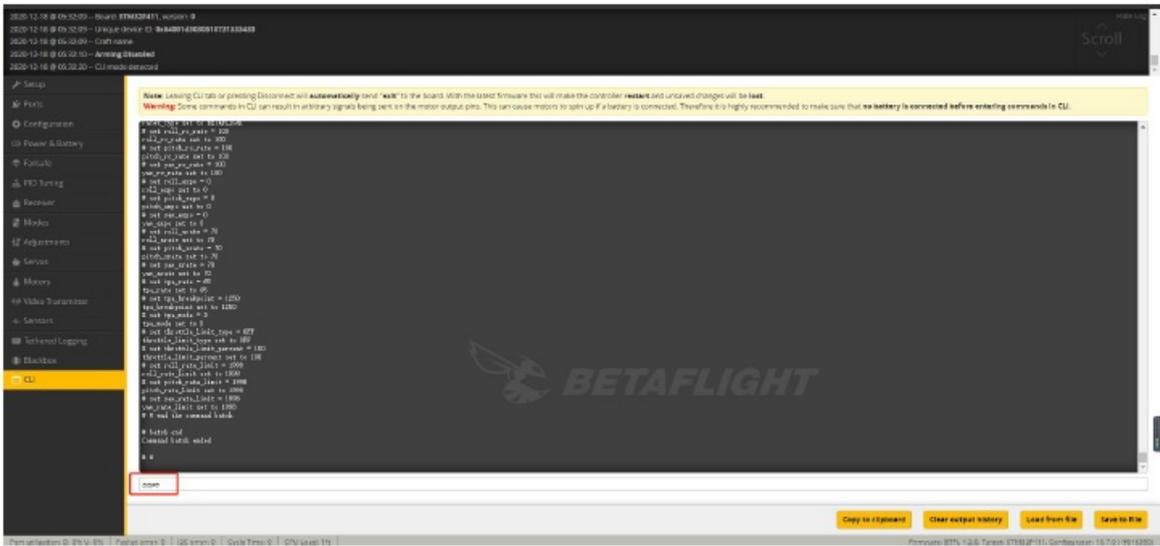
3. Then load the local HEX firmware and wait for the flashing to complete. A green progress bar is displayed to indicate completion, and DFU will become a COM port



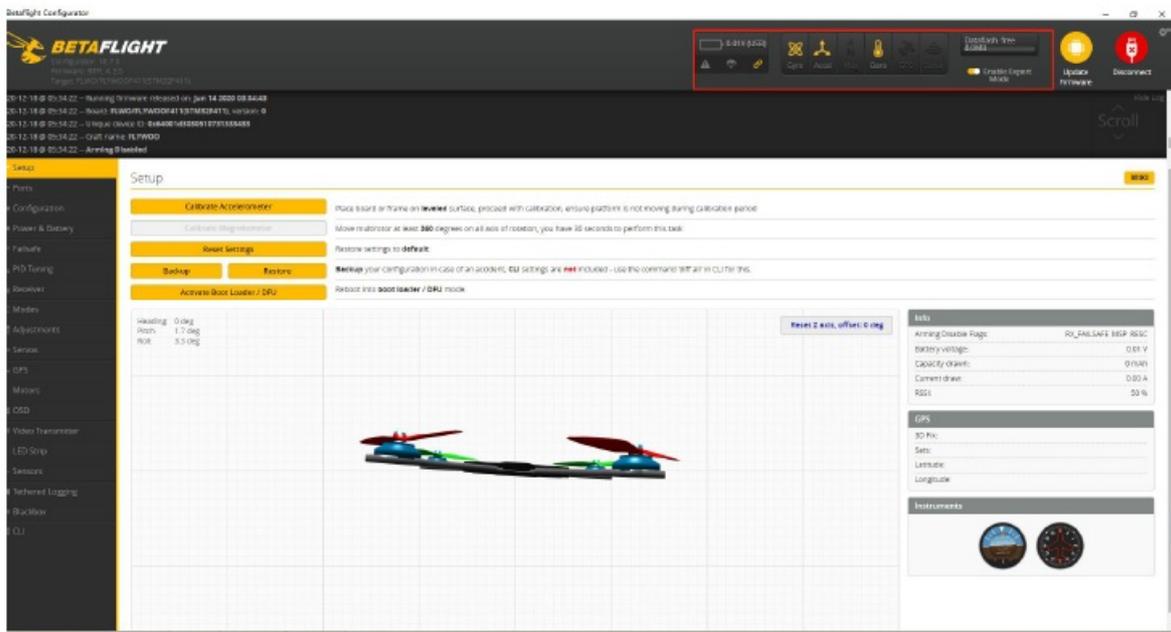
4. After the connection is entered, it is a blank interface, you need to write CLI commands, Factory CLI LINK: <https://flywoo.net/pages/manual>



5. If the command is not restarted after writing the command, please write SAVE and press Enter to save, and the FC will restart



6. Then all functions of FC return to normal.



Documents / Resources

 <p>FLYWOO EXPLORER LR 4 Manual Analog Version</p>	<p>FLYWOO LR4 EXPLORER QUAD ANALOG [pdf] User Manual LR4 EXPLORER QUAD ANALOG, EXPLORER QUAD ANALOG, QUAD ANALOG</p>
---	--

References

- [FLYWOO](#)
- impulserc.blob.core.windows.net/utilities/ImpulseRC_Driver_Fixer.exe

