



KDE Direct PIXHAWK PX4 Series UAS Electronic Speed Controller Instructions

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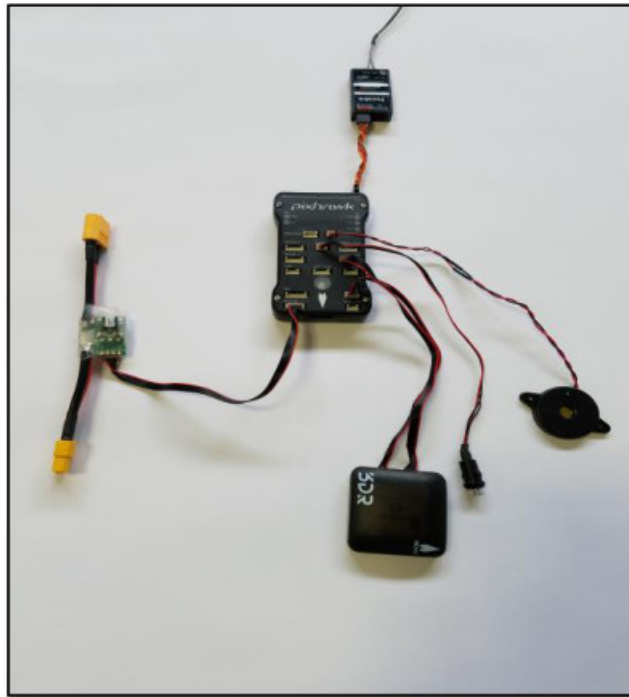
PIXHAWK PX4 Series

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PIXHAWK PX4 Series UAS Electronic Speed Controller

Please follow the instructions for proper installation, wiring, and programming of the KDE Direct UAS Electronic Speed Controller (ESC) series to the Pixhawk and PX4 open-hardware project autopilot.



PIXHAWK (PX4)EQUIPMENT

The Pixhawk (PX4) autopilot is powered via the power module (PMU) included with the system for multi-platform autonomous vehicles. For additional information on the correct installation of the autopilot equipment, please reference the

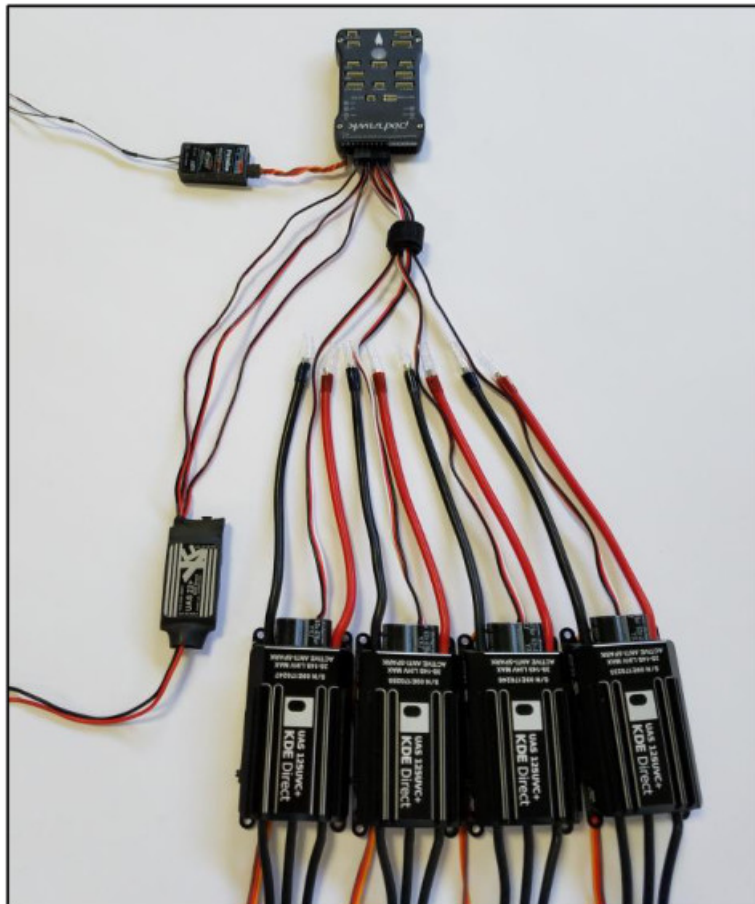
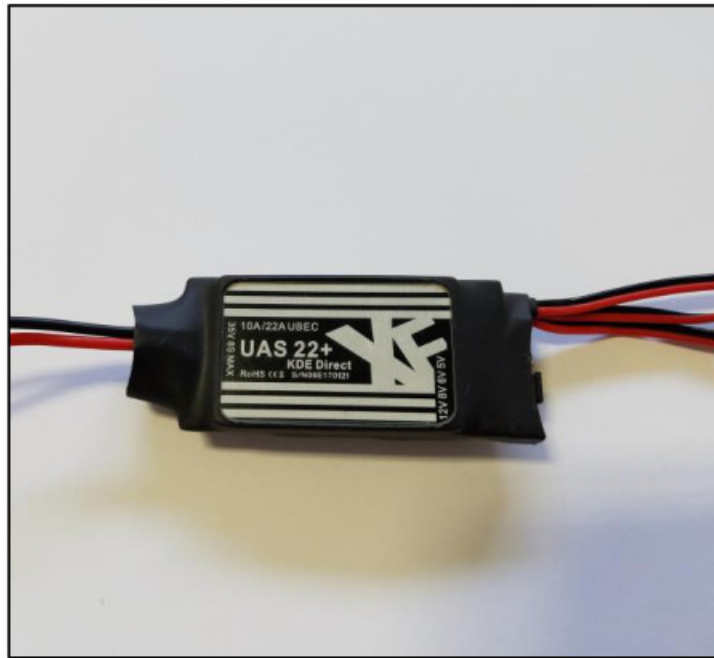
[Pixhawk Autopilot Website](#).

Due to the hardware design of the Pixhawk (PX4) autopilot, power is NOT provided to the ESCs via the MAIN OUT control-lead signal ports.

The KDE Direct UAS ESCs are OPTO-Isolated and therefore, require a 5V or 6V external powerline to properly arm the internal circuitry critical for safe flight operation. As a reference, the UAS ESC OPTO-Isolation circuitry is compatible up to 35V maximum-input.

KDE DIRECT UAS ESC OPTO-ISOLATION CIRCUITRY

To provide clean, voltage-regulated power for the KDE Direct UAS ESCs, the KDEXF-UBEC22 is available for direct compatibility to the electronics. During assembly, set the voltage-selection jumper to 6V as shown – please review the Instruction Manual (included with purchase and found under the webpage Technical Media tab) for additional details on proper installation and wiring of the device.



ESC HARDWARE INSTALLATION AND WIRING

For Quadcopter systems (X-4), please reference the image for proper installation of the control wiring. For the complete installation, the Pixhawk (PX4) autopilot, KDE Direct UAS UBEC, KDE Direct UAS ESCs, and Futaba™ Receiver (S.BUS RX) components are shown for reference.

The KDE Direct KDEXF-UBEC22 incorporates three (3) power-output leads as standard, providing redundant power lines as desired to the MAIN OUT control-lead signal ports. In this configuration, three (3) of the power-output leads will be used for simplistic installation and triple-redundancy.

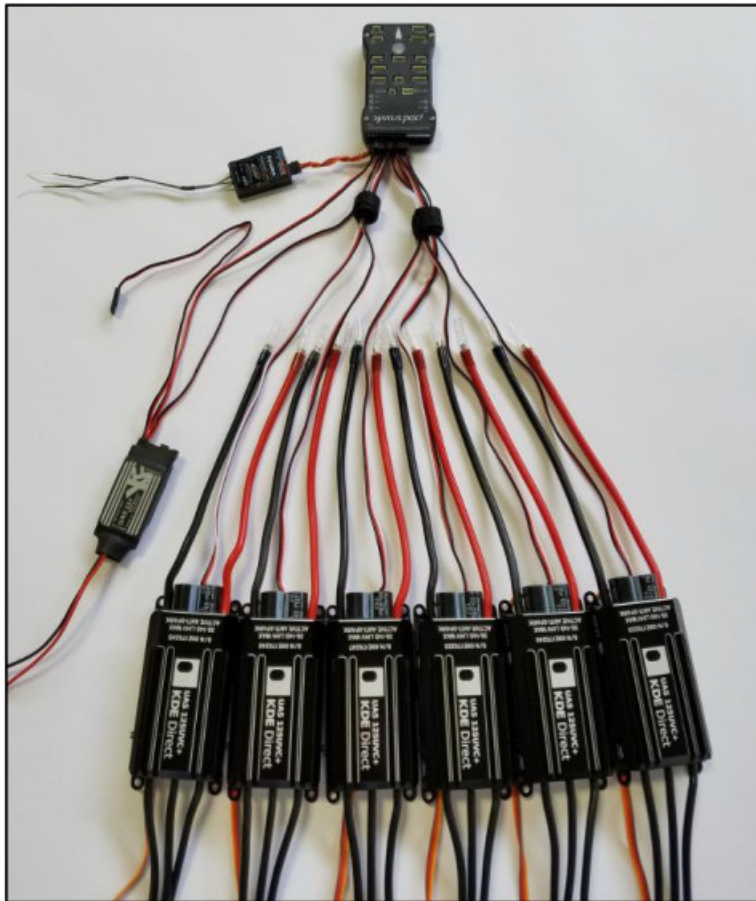
At a minimum, one (1) power-output lead is required to provide the necessary 5V or 6V power for proper operation of the KDE Direct UAS ESCs.

PIXHAWK (PX4) CONNECTION OUTPUTS AND PORTS

For Quadcopter systems, please reference the proper connection as:

- UAS ESC control-leads connected into ports “1 – 4”
- UAS UBEC power-leads connected into ports “5 – 7”
- (triple-redundant layout)
- PPM/S.BUS (RX) connected into port “RC”





PIXHAWK (PX4) CONNECTION OUTPUTS AND PORTS

For Hexacopter systems, please reference the proper connection as:

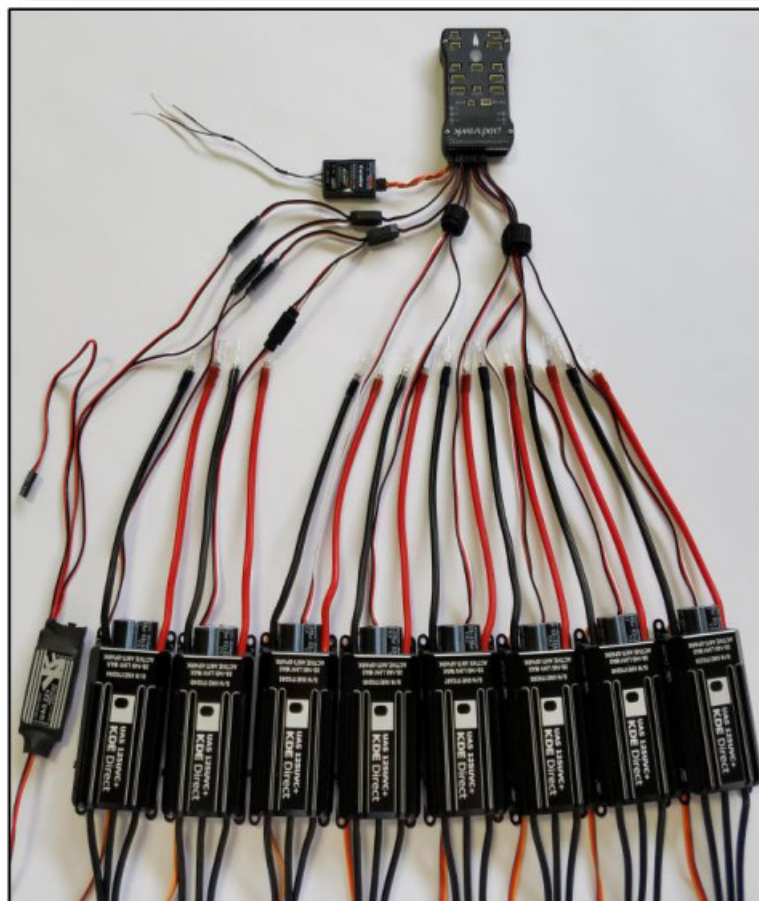
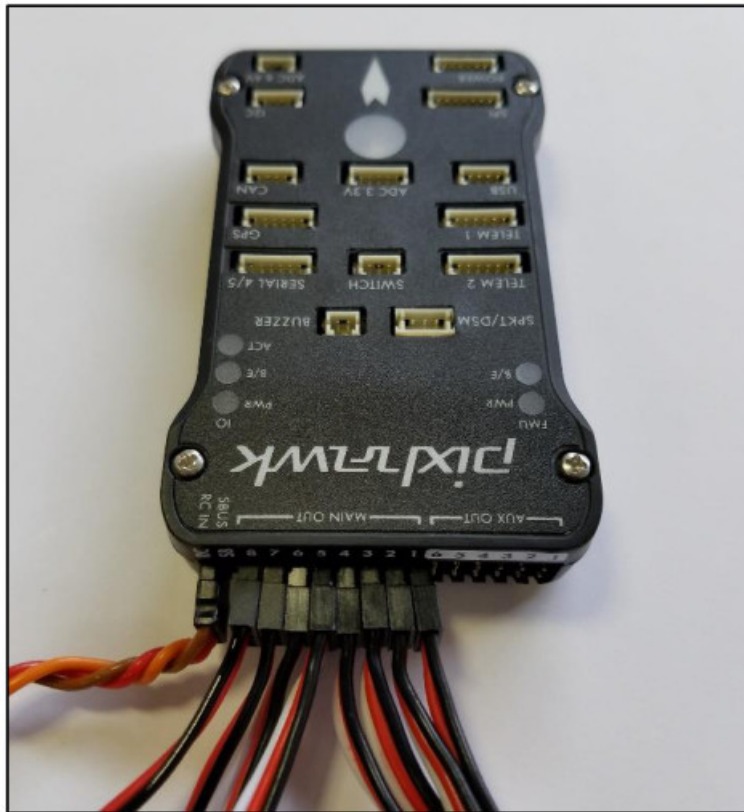
- UAS ESC control-leads connected into ports “1 – 6”
- UAS UBEC power-leads connected into ports “7 – 8”
- (dual-redundant layout)
- PPM/S.BUS (RX) connected into port “RC”

ESC HARDWARE INSTALLATION AND WIRING

For Hexacopter systems (including Y-6 and D-12 coaxial), please reference the image for proper installation of the control wiring. For the complete installation, the Pixhawk 2.1 (CUBE) autopilot, KDE Direct UAS ESCs, and Futaba™ Receiver (S.BUS RX)

components are shown for reference. The KDE Direct KDEXF-UBEC22 incorporates three (3) power-output leads as standard, providing redundant power lines as desired to the MAIN OUT control-lead signal ports. In this configuration, three (3) of the power-output leads will be used for simplistic installation and triple-redundancy.

At a minimum, one (1) power-output lead is required to provide the necessary 5V or 6V power for proper operation of the KDE Direct UAS ESCs.



PIXHAWK (PX4) CONNECTION OUTPUTS AND PORTS

For Octocopter systems, please reference the proper connection as:

- UAS ESC control-leads connected into ports “1 – 8”
- UAS UBEC power-leads connected into ports “7 – 8”
- (dual-redundant layout, y-harness adapters)

- PPM/S.BUS (RX) connected into port “RC”

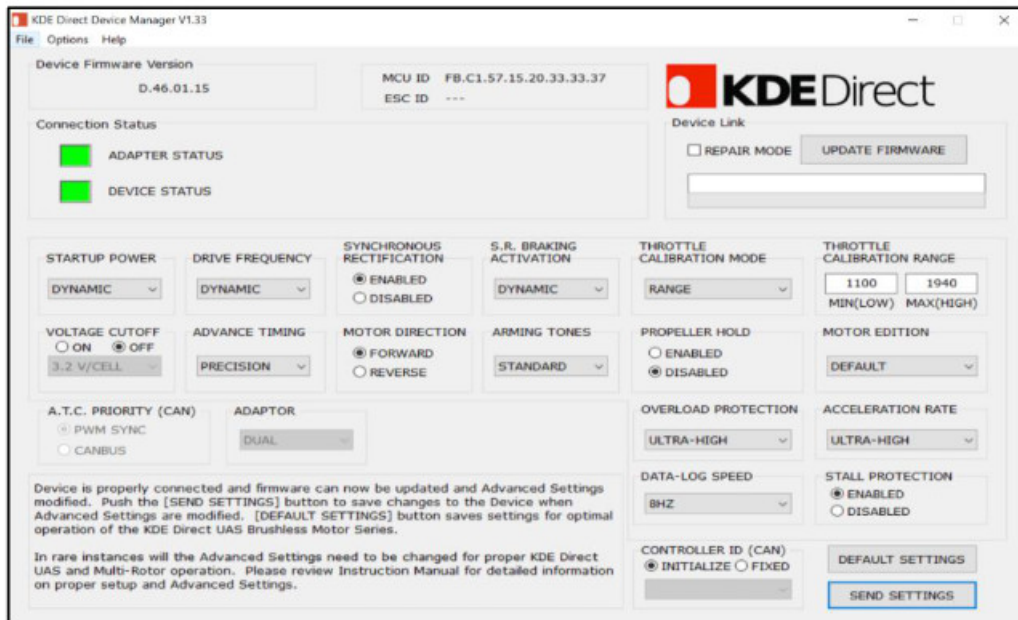
At a minimum, one (1) power-output lead is required to provide the necessary 5V or 6V power for proper operation of the KDE Direct UAS ESCs.

For Octocopter systems (including X-8 and H-16 Coaxial), please reference the image for proper installation of the control wiring. For the complete system, the Pixhawk (PX4) autopilot, KDE Direct UAS UBEC, KDE Direct ESCs, and Futaba™ Receiver (S.BUS RX) components are shown for reference.

The KDE Direct KDEXF-UBEC22 incorporates three (3) power-output leads as standard, providing redundant power lines as desired to the MAIN OUT control-lead signal ports. In this configuration, two (2) of the power-output leads will be used for simplistic installation via dual Y-harness adapters to any ESC control-leads (ports 7 and 8 used in this example). The additional third power-output lead can be connected via a Y-harness to any ESC control-lead if desired, or can be used for alternate electronics as needed (such as a 5V/6V camera or redundant power to the RX).



The KDE Direct UAS Electronic Speed Controller (ESC) series is programmable via the [KDEXF-DMA Device Manager Adapter | UAS Electronic Speed Controller | KDE Direct](#) (available separately) or direct via PC-USB connection (UVC Series), providing the ability for updates to the latest firmware releases and customize advanced options. Please review the Instruction Manual (found under the webpage Specifications tab) for detailed information on Advanced Settings.



ARDUPILOT MISSION PLANNER SOFTWARE

After programming all KDE Direct UAS ESCs to the RANGE mode as described above, setup of the Pixhawk (PX4) via the Mission Planner software can proceed. The manual throttle calibration process is not needed via the RANGE mode – simply hard-code the settings of Output PWM Min = 1100 and Output PWM Max = 1940 as shown. For additional information on the correct programming and operation of the Mission Planner software, please reference the Mission Planner Home Website.

KDE DIRECT DEVICE MANAGER SOFTWARE


For direct compatibility to the Pixhawk (PX4) autopilot, change the “THROTTLE CALIBRATION MODE” to RANGE via the selectable pulldown menu. This will allow for a fixed throttle calibration to the autopilot, for simple programming via the ArduPilot Mission Planner software and Radio/ESC Calibration wizard. Within the “THROTTLE CALIBRATION RANGE” option, use the default settings of MIN(LOW) = 1100 and MAX(HIGH) = 1940.








Note: program the “ESC Type” to “Normal” for synchronization of autopilot gyros and ESC control frequencies

(400 Hz dynamic).

Documents / Resources

	KDE Direct PIXHAWK PX4 Series UAS Electronic Speed Controller [pdf] Instructions KDE-UAS125UVC, PIXHAWK PX4 Series UAS Electronic Speed Controller, PIXHAWK PX4 Series, UAS Electronic Speed Controller, Electronic Speed Controller, Speed Controller, Controller
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References

-  [Mission Planner Home — Mission Planner documentation](#)
-  [Pixhawk | The hardware standard for open-source autopilots](#)
-  [KDE-DMS Device Manager Software | UAS Electronic Speed Controller | KDE Direct](#)
-  [KDEXF-DMA Device Manager Adapter | UAS Electronic Speed Controller | KDE Direct](#)
-  [KDEXF-UBEC22 22A+ UBEC | UAS Universal Battery Eliminator Circuit | KDE Direct](#)

Manuals+.