

Gannet Pro Remote Controller





Controls;

Top left outer button, Lock/ Unlock image. Bait release. (picture above)

This button will release the electronic release system on flipping the switch. **(PLEASE ensure that you set the mechanical safety to the correct weight prior to flying for your drone's safety.)**

Top left inner button, Teardrop image. Auto flip of the drone if it lands in the water and is upside down. IF the drone is upside down in the water toggle this button 3 times in succession and release, wait for the drone to correct it's self. This happens by the system starting motor number 3 only to correct the drone.



Top right outer button, GPS, ATTI, RTH (picture above)

This is to set the flight mode,

GPS; fully automated flight control, this means the flight controller will maintain position, attitude, altitude and height and will also correct for wind.

ATTI; semi automated flight control, the flight controller will maintain attitude but the pilot will be required to correct for wind and height.

RTH; return to home position, this will cause the drone to climb to the preset RTH height and the fly to the take off position, hover and auto land.

(PLEASE note this is an emergency use only, it is not recommended by Gannet or DJI (NAZA) as the normal way to return your drone after a drop.)

Top right inner button; NOR, CL, HL (IOC)

The following is from the MV2 quick start guide.

A3 Intelligent Orientation Control (IOC) Flight (with GPS module)

Definition of Forward Direction:

Multi-rotor will fly along this direction when you push the elevator stick ().

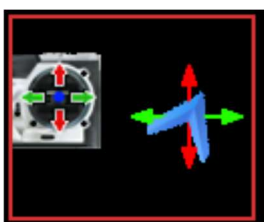
Step 1 Before You Start

Usually, the forward direction of a flying multi-rotor is the same as the nose direction. By using IOC, wherever the nose points, the forward direction has nothing to do with nose direction. The red and blue arrows on the transmitter are corresponding to pitch and roll operations in the following diagram.

☑ In course lock flying, the forward direction is the same as a recorded nose direction. All the following requirements are met: the autopilot system is in ATTI. Mode or GPS ATTI. Mode.

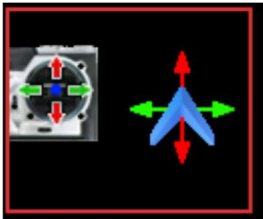


Normal flying

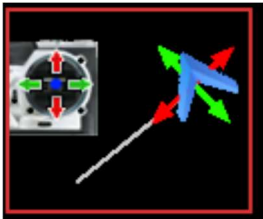


Course Lock Flying

In home lock flying, the forward direction is the same as the direction from home point to multi-rotor. All the following requirements are met: 6 or more GPS satellites are found, in GPS ATTI. Mode, and the aircraft is further than 10m away from the home point.



Normal flying



Home Lock Flying

Control sticks; (All descriptions are looking forwards from the back of the drone, or as if you were sitting in the drone.)

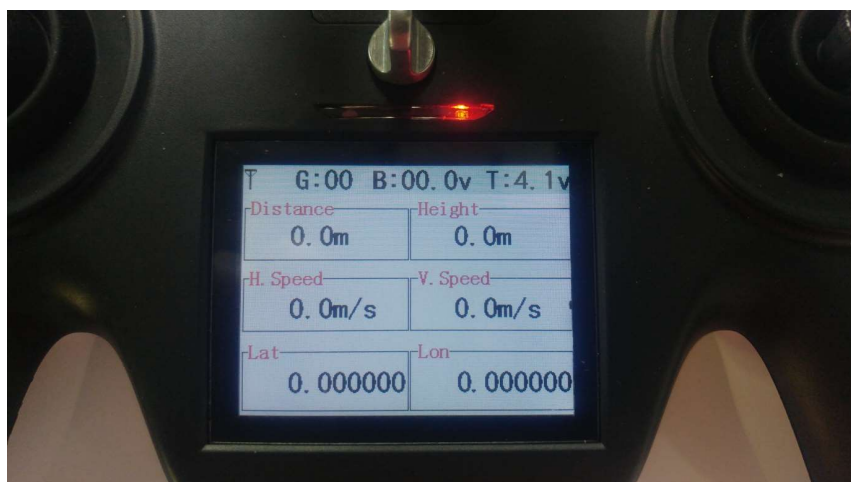
Left stick; Up and Down this will control the ascent and descent of the drone. After takeoff if the stick is central the drone will hover.

Left stick; Left and Right, this will control the yaw, turn the nose of the drone left or right looking forwards from the back of the drone.

Right stick: Up and Down, this will control the pitch of the drone, stick up will tilt the drone forwards causing forward flight. Pulling the stick back will tilt the drone to the rear causing reverse flight.

Right Stick: Left and Right, this will control the Roll of the drone, stick left will tilt the drone to the left causing sideways flight to the left. Stick right will tilt the drone to the right causing sideways flight to the right.

Screen



This shows:

Signal

G: Number of satellites

B: Drone battery voltage

T: Transmitter battery voltage

Distance: Distance from takeoff point

Height: Height from takeoff point

Lat/Lon: current geographical position.

If you press the power button twice you will get the screen below to show you servo positions, this is a test only screen and is only to show that the signals for each channel are correct.

