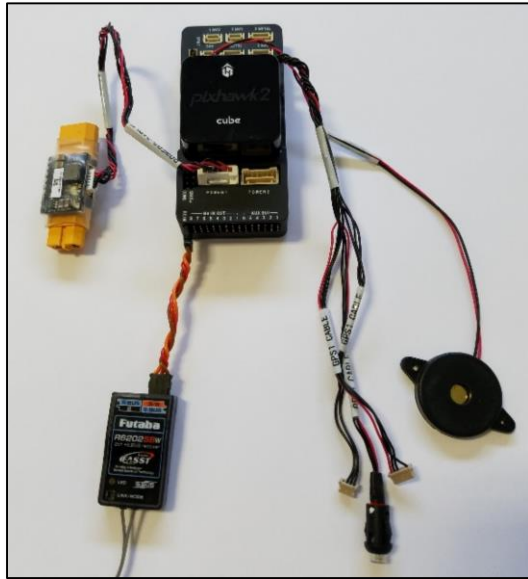


KDE Direct

PIXHAWK (2.1 CUBE) SERIES

[+]

Please follow the instructions for proper installation, wiring, and programming of the KDE Direct UAS Electronic Speed Controller (ESC) series to the Pixhawk 2.1 (CUBE) and PX4 open-hardware project autopilot.



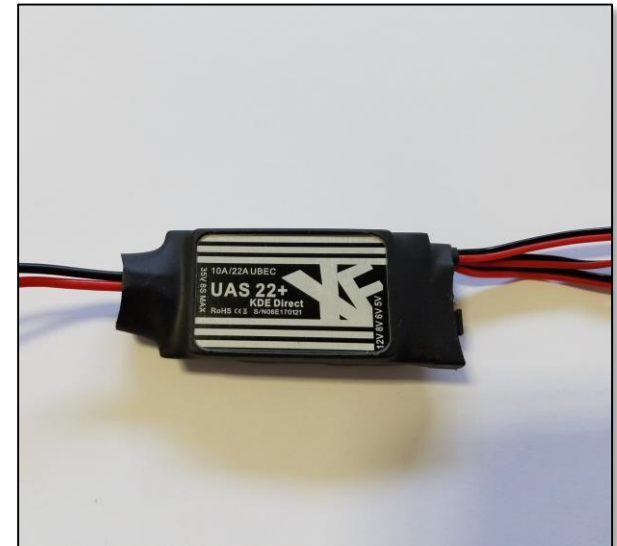
PIXHAWK 2.1 (CUBE) EQUIPMENT

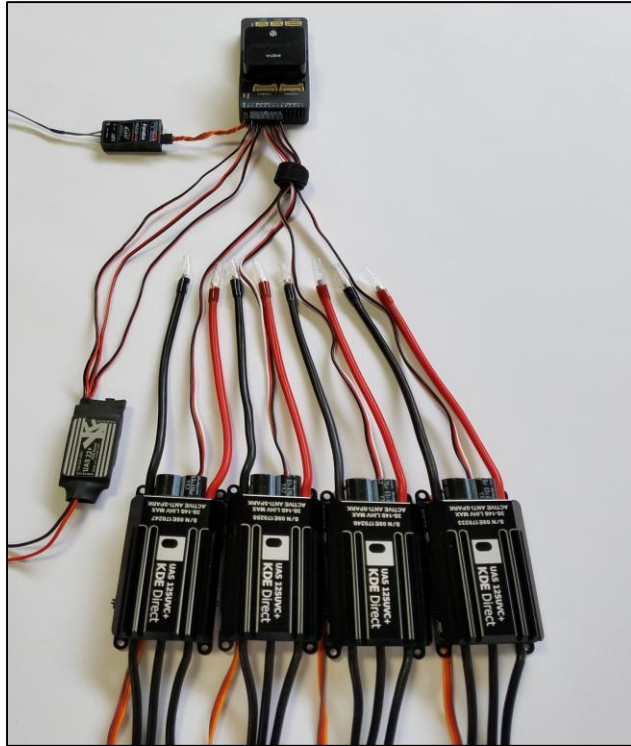
The Pixhawk 2.1 (CUBE) autopilot is powered via the power module (PMU) included with the system for multi-platform autonomous vehicles. For additional information on the correct installation of the autopilot equipment, please reference the [Pixhawk Autopilot Website](#).

While the MAIN OUT power of the Pixhawk 2.1 (CUBE) is sufficient to arm the ESCs, we strongly recommend using the [KDEXF-UBEC22](#) with the Pixhawk 2.1 (Cube). The [KDEXF-UBEC22](#) ensures optimal voltage and enhances the reliability of your system.

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 2.1 (CUBE) autopilot, KDE Direct UAS ESCs, and Futaba™ Receiver (S.BUS RX) 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.

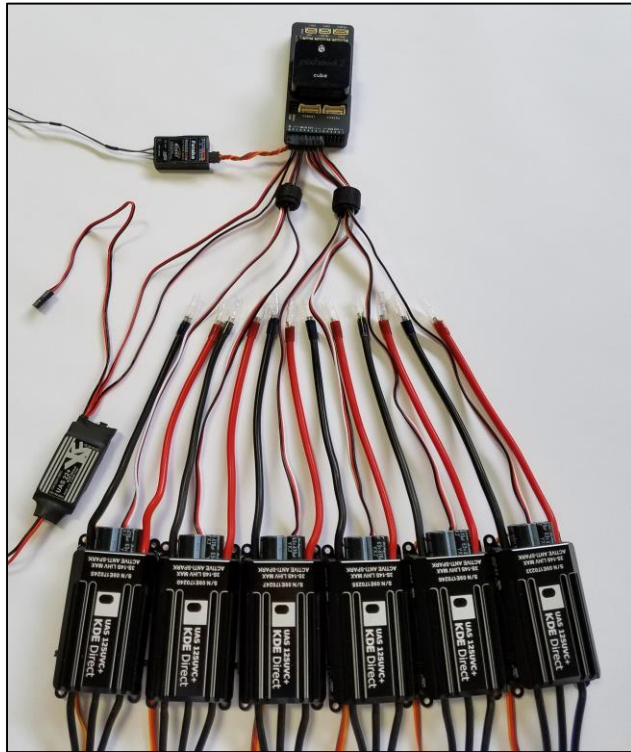
At a minimum, one (1) power-output lead is required to provide the necessary 5V or 6V power for proper operation of the KDE Direct UAS ESCs.

PIXHAWK 2.1 (CUBE) 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”





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.

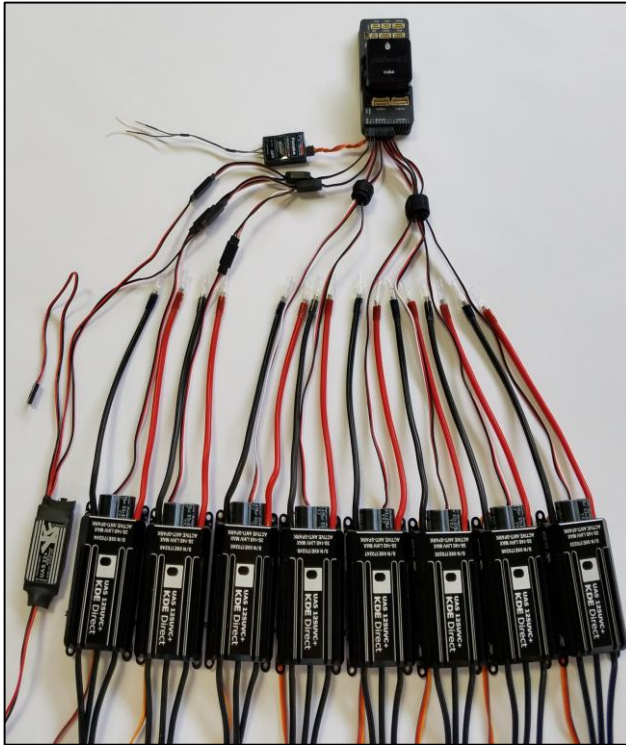
At a minimum, one (1) power-output lead is required to provide the necessary 5V or 6V power for proper operation of the KDE Direct UAS ESCs.

PIXHAWK 2.1 (CUBE) 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 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 2.1 (CUBE) autopilot, KDE Direct ESCs, and Futaba™ Receiver (S.BUS RX) are shown for reference.

Check for correct orientation of the control leads to the Pixhawk 2.1 autopilot as shown below, keeping the red-wire intact for all leads.

PIXHAWK 2.1 (CUBE) 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.

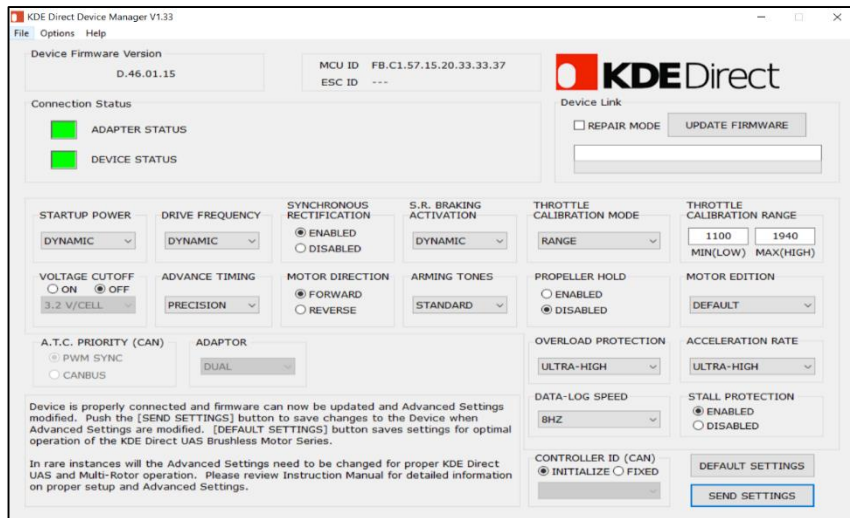


KDE Direct

PIXHAWK (2.1 CUBE) SERIES



The KDE Direct UAS Electronic Speed Controller (ESC) series is programmable via the [KDEXF-DMA Programming Kit](#) (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.



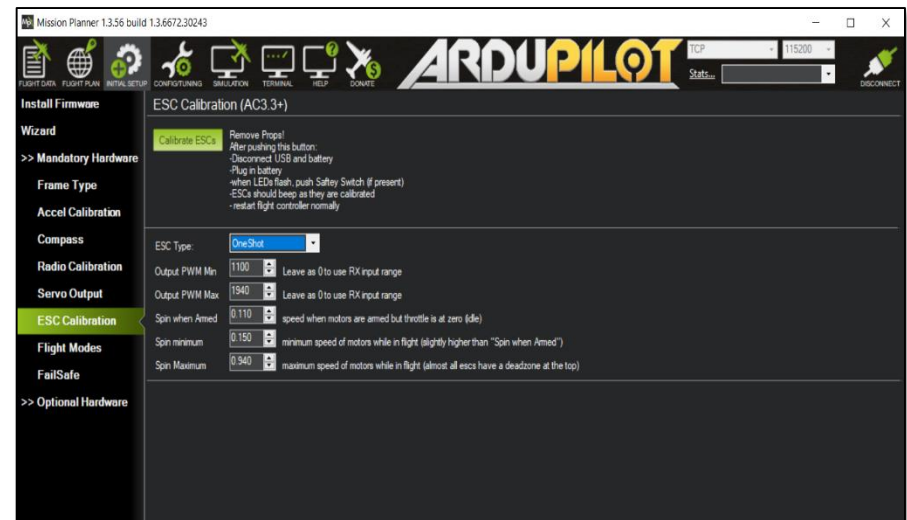
KDE DIRECT DEVICE MANAGER SOFTWARE

For direct compatibility to the Pixhawk (PX4) autopilot, change the “THROTTLE CALIBRATION MODE” to RANGE via the selectable pull-down 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.

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.



Note: program the “ESC Type” to “OneShot” for synchronization of autopilot gyros and ESC control frequencies (400 Hz dynamic).

For additional information on the correct programming and operation of the Mission Planner software, please reference the [Mission Planner Home Website](#).