

M470 *Super Combo*
MULTICOPTER

ALIGN

INSTRUCTION MANUAL

使用說明書

RM47001XT

Windows



ANDROID APP ON

Google play



Download on the
App Store



Camera not included



For more detailed instructions,
please check our website.

<http://www.align.com.tw/multicopter-en/m470/>

更詳細的組裝說明請上官網。

Congratulations on your purchase of Align M470 multicopter! The M470 is a representation of the latest technology in rotary RC models. Please consult this manual carefully before assembling and flying the new M470 multicopter. We recommend that you keep this manual as a tuning and maintenance reference for future use.

承蒙閣下選用亞拓多軸航拍機系列產品，謹表謝意。進入遙控世界之前必須告訴您許多相關的知識與注意事項，以確保您能夠在使用的過程中較得心應手。在開始操作之前，請務必詳閱本說明書，相信一定能夠給您帶來相當大的幫助，也請您妥善保管這本說明書，以作為日後參考。



GPS

4MODES



Smart

OSD



S.BUS

X.BUS

iOS

Android

Blue tooth

RoHS

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INTRODUCTION

前言

ALIGN

We appreciate your patronage of Align products. To ensure your success with this product, we would like to present the following information and important reminders.

Align Multicopter represents the latest innovation in multi-rotor aircraft design.

Amongst its design features:

Innovative, streamlined splash resistant shape at the pinnacle of power and beauty, industrial and structural design. Encompass stability control system, features light weight, strong payload, and long flight time. Superior in both high speed agility and static stability, this multi-purposed professional multicopter exceeds in all areas such as aerial photography or as leisurely sports flyer; yet its light weight allows for easy transport anywhere.

In order for you to thoroughly enjoy the Multicopter experience, please read through this manual prior to assembly and setting up the M470 Multicopter. Please keep this manual handy for future reference.

承蒙閣下選用亞拓遙控世界系列產品，謹表謝意。進入遙控世界之前必須告訴您許多相關的知識與注意事項，以確保您能夠在學習的過程中較得心應手。

亞拓多軸飛行機的設計特點為：

前衛流線防潑水造型，極致力與美，工業與結構設計，搭配穩定控制系統，輕量載重力強、飛行時間長特點，其動/靜皆強的高速運動飛行與穩定特性，兼具航拍、娛樂、休閒、攜帶輕便多用途專業多軸飛行機。

為了讓您容易方便使用，在開始操作之前，請您詳細的閱讀完這本說明書之後再進行安裝與設定，同時請您妥善保存這本說明書，作為爾後調整的參考。

QR CODE LINKS TO INSTRUCTIONAL VIDEOS

QR CODE教學影片

While this manual provides instructional information and references for this product, Align also produced instructional videos covering various topics pertaining to this model. The videos are available at the following link:

<http://www.align.com.tw/m470vid-en/>

說明書詳細介紹了本產品的使用說明，供您組裝時參考。另外，亞拓提供了各步驟的組裝教學影片，請利用下方連結處觀看，以確保您是安全且正確的使用本產品。

網頁瀏覽<http://www.align.com.tw/m470vid-en/>

Assembly Tutorial 組裝教學	PC Interface Program Download Tutorial 介面下載教學	Configuration Tutorial 設定教學	Operation Tutorial 操作教學
			

IMPORTANT NOTES

重要聲明

ALIGN

Radio Control (R/C) multicopters are not toys. R/C multicopters utilize various high-tech components to achieve superior performance. Improper use of this product can result in serious injury or even death. Please read this manual carefully before operating, and make sure to be conscious of your own personal safety and the safety of others nearby when operating all ALIGN products. Manufacturer and seller assume no liability for the operation or the use of this product. This product is intended for use only by adults with experience flying remote control aircraft at legal flying fields. After the sale of this product we cannot be held liable over its operation or usage.

We recommend that you seek the assistance of an experienced pilot before attempting to fly our products for the first time. A local expert is the best way to properly assemble, setup, and fly your model for the first time. This product requires a certain degree of skill to operate, and is an expendable item. Any damage or dissatisfaction as a result of accidents or modifications are not covered by any warranty and cannot be returned for repair or replacement. Please contact our distributors for free technical consultation and parts at discounted rates when you experience problems during operation or maintenance. As Align Corporation Limited has no control over the use, setup, assembly, modification or misuse, no liability shall be assumed nor accepted for any resulting damage or injury. By the act of use, setup or assembly, the user accepts all resulting liability.

In addition, R/C multicopters and its components are precision electronics susceptible to interferences from external forces such as magnetic field and radio signal. Should the multicopter or any onboard photographic equipment suffers loss or crash damage as result of external magnetic or radio interferences, Align cannot be held liable as the cause is beyond our control.

As the user of this product, you are solely responsible for operating in a manner that does not endanger yourself and others or result in damage to the property of others.




遙控飛行機包括遙控直昇機與多軸飛行機（以下簡稱遙控飛行機）並非玩具，它是結合了許多高科技產品所設計出來的休閒用品，所以商品的使用不當或不熟悉都可能造成嚴重傷害甚至死亡，使用之前請務必詳讀本說明書，勿輕忽並注意自身安全。注意！任何遙控飛行機的使用，製造商和經銷商是無法對使用者於零件使用的損耗異常或組裝不當所發生之意外負任何責任，本產品是提供給有操作過遙控飛行機經驗的成人或有相當技術的人員在旁指導，並於當地合法遙控飛行場飛行，以確保安全無虞下操作使用。產品售出後本公司將不負任何操作和使用控制上的任何性能與安全責任。

遙控飛行機屬於需高操作技術且為消耗性之商品，如經拆裝使用後，會造成不等情況零件損耗，任何使用情況所造成商品不良或不滿意，將無法於保固條件內更換新品或退貨，如遇有使用操作維修問題，本公司全省分公司或代理商將提供技術指導、特價零件供應服務。對使用者的不當使用、設定、組裝、修改、或操作不良所造成的破損或傷害，本公司無法控制及負責。且遙控飛行機與配件之精密電子產品，易受外力、磁場、訊號干擾，在使用過程中如外力、磁場、訊號干擾，導致飛行機本身、及其搭載之攝影設備、器材之損壞或滅失，本公司亦無法控制及負責。

做為本產品的使用者，您，是唯一對於您自己操作的環境及行為負全部的責任之人。

WARNING LABEL LEGEND

標誌代表涵義

 FORBIDDEN 禁止	Do not attempt under any circumstances. 在任何禁止的環境下，請勿嘗試操作。
 WARNING 警告	Mishandling due to failure to follow these instructions may result in serious damage or injury. 因為疏忽這些操作說明，而使用錯誤可能造成財產損失或嚴重傷害。
 CAUTION 注意	Mishandling due to failure to follow these instructions may result in danger. 因為疏忽這些操作說明，而使用錯誤可能造成危險。

SAFETY NOTES

安全注意事項

ALIGN

- Fly only in safe areas, away from other people. Do not operate R/C aircraft indoors or within the vicinity of homes or crowds of people. R/C aircraft are prone to accidents, failures, and crashes due to a variety of reasons including: lack of maintenance, pilot error, and radio interference. Pilots are responsible for their actions and damage or injury occurring during the operation or as of a result of R/C aircraft models.
- Prior to every flight, carefully check all parts such as blades, screws, frame, arms, etc; ensure they are firmly secured and show no unusual wears, or unforeseen danger may happen.
- 遙控飛行機屬高危險性商品，飛行時務必遠離人群，禁止於室內飛行。人為組裝不當或未定期檢修造成的機件損壞、電子控制設備不良，以及操控上的不熟悉、都有可能導致飛行失控損傷等不可預期的意外，請飛行者務必注意飛行安全，並需了解自負疏忽所造成任何意外之責任。
- 每趟飛行前須仔細檢查機身各部位之零/配件/電子設備之性能是否正常，及無損耗老化現象，並確實將螺絲鎖緊才能升空飛行。並做好定期檢修，避免零件或電子產品異常所造成不可預期意外。



FORBIDDEN
禁止

LOCATE AN APPROPRIATE LOCATION

遠離障礙物及人群

R/C aircraft can fly at high speed, thus posing a certain degree of potential danger. Choose a legal flying field consisting of flat, smooth ground without obstacles. Do not fly near buildings, high voltage cables, or trees to ensure the safety of yourself, others, and your model. Avoid location with magnetic and radio interferences. Please choose a legal flying field. Do not fly your model in inclement weather, such as rain, wind, snow or darkness.

遙控飛行機飛行時具有一定的速度，相對的也潛在著危險性，場地的選擇也相對的重要，請需遵守當地法規到合法遙控飛行場地飛行。必須注意周遭有沒有人、高樓、建築物、高壓電線、樹木等等，避免磁場干擾、外力訊號干擾及操控的不當造成自己與他人財產的損壞。請務必選擇在空曠合法專屬飛行場地。請勿在下雨、打雷、沙塵等惡劣天候下操作，以確保本身及機體的安全。



FORBIDDEN
禁止

NOTE ON LITHIUM POLYMER BATTERIES

鋰聚電池注意事項

Lithium Polymer batteries are significantly more volatile than alkaline or Ni-Cd/Ni-MH batteries commonly used in RC applications. All manufacturer's instructions and warnings must be followed closely. Mishandling of Li-Po batteries can result in fire. Always follow the manufacturer's instructions when disposing of Lithium Polymer batteries.

鋰聚電池跟一般在RC使用的鹼性電池、鎳鎘電池、鎳氫電池比較起來是相對危險的。請嚴格遵守鋰聚電池說明書之使用注意事項。不恰當使用鋰聚電池，可能造成火災並傷及生命財產安全，切勿大意！



FORBIDDEN
禁止

PREVENT MOISTURE

遠離潮濕環境

R/C aircraft are composed of many precision electrical components. It is critical to keep the model and associated equipment away from moisture and other contaminants. The introduction or exposure to water or moisture in any form can cause the model to malfunction resulting in loss of use, or a crash. Do not operate or expose to rain or moisture.

遙控飛行機內部也是由許多精密的電子零組件組成，所以必須絕對的防止潮濕或水氣，避免在浴室或雨天時使用，防止水氣進入機身內部而導致機件及電子零件故障而引發不可預期的意外！





FORBIDDEN 禁止 PROPER OPERATION 勿不當使用本產品

Do not attempt to modify the aircraft to alter its intended design. Please use only designated replacement parts listed in the manual to ensure its design structure integrity. Operate this product within its intended design parameters; do not overload it with excess cargo. This product is limited to personal hobby use, and pilot should be proficient with operation of this model. Follow all local law and ordinances when operating. Do not use this product for purposes which may violate others' personal privacy, and respect other's intellectual properties. Do not use this product for illegal purposes or beyond the bonds of common safety.

請勿自行改造加工，任何的升級改裝或維修，請使用亞拓產品目錄中的零件，以確保結構的安全。請確認於產品限界內操作，請勿過載使用，本產品為休閒娛樂專用之精密電子遙控飛行產品，僅限熟練遙控飛行器之個人使用，使用時請遵守當地法律規定，並嚴禁在任何違反公共安全區域操作，請勿利用本產品侵犯他人隱私/公開權、並尊重他人智慧財產權、著作權，且勿用於安全、法令外之其它非法用途。並充分了解您任何的使用與操作必須負完全的責任。



WARNING 警告 DO NOT FLY ALONE 避免獨自操控

Before turning on your model and transmitter, check to make sure no one else is operating on the same frequency. Frequency interference can cause your model, or other models to crash. The guidance provided by an experienced pilot will be invaluable for the assembly, tuning, trimming, and actual first flight or unforeseen danger may happen. (Recommend you to practice with experienced pilots or with computer-based flight simulator firstly.)

至飛行場飛行前，需確認是否有相同頻率的同好正進行飛行，因為開啓相同頻率的發射機將導致自己與他人立即干擾等意外危險。遙控飛行機操控技巧在學習初期有著一定的難度，要盡量避免獨自操作飛行，需有經驗的人士在旁指導，才可以操控飛行，否則將可能造成不可預期的意外發生。(勤練電腦模擬器及老手在場指導是入門必要的選擇)



WARNING 警告 SAFE OPERATION 安全操作

Operate this unit within your ability. Do not fly while feeling impaired, as improper operation may result in danger. Never take your eyes off the model or leave it unattended while it is turned on. Immediately turn off the model and transmitter when you have landed the model.

請於自己能力內及需要一定技術範圍內操作這台遙控飛行機，過於疲勞、精神不佳或不當操作，意外發生風險將可能會提高。不可在視線範圍外飛行，降落後也請馬上关掉遙控飛行機和遙控器電源。



CAUTION 注意 ALWAYS BE AWARE OF THE ROTATING BLADES 遠離運轉中零件

During the operation of the multicopter, the rotor will be spinning at a high rate of speed. The blades are capable of inflicting serious bodily injury and damage to surrounding properties. Be conscious of your actions, and careful to keep your face, eyes, hands, and loose clothing away from the blades. Always fly the model a safe distance from yourself and others, as well as surrounding objects.

遙控飛行機主旋翼/螺旋槳運轉時會以高轉速下進行，在高轉速下的主旋翼/螺旋槳會造成自己與他人在身體上或環境上的嚴重損傷，請勿觸摸運轉中的主旋翼/螺旋槳，並保持安全距離以避免造成危險及損壞。





KEEP AWAY FROM HEAT 遠離熱源

R/C aircraft are made of various forms of plastics, such as carbon fiber and polyethylene. Plastics are very susceptible to damage or deformation from extreme heat and cold climate. Make sure not to store the model near any source of heat such as oven or heater. It is best to store the model indoors, in a climate-controlled, room temperature environment.

遙控飛行機多半是以碳纖維、PA 纖維或聚乙烯、電子商品為主要材質，因此要盡量遠離熱源、日曬，以避免因高溫而變形甚至熔毀損壞的可能。



EQUIPMENT REQUIRED

自備設備

ALIGN

1 RADIO TRANSMITTER AND ELECTRONIC EQUIPMENT REQUIRED

自備遙控及電子設備



R/C Transmitter (8-channel or more, aircraft / multicopter system)
發射機 (八動以上具飛機/多軸模式遙控器)



Receiver (8 channel or more)
接收器 (八動作以上)



or
或



Satellites Receiver
衛星天線



Suitable RC transmitter for multicopter use must have at least 8 channels, with two 2-position switches and two 3-position switches. Suitable RC transmitter for multicopter and gimbal use must have at least 10 channels, with two 2-position switches, two 3-position switches, and two slider controls.

操控多軸機飛行時，須搭配使用八動以上遙控器，具備2支兩段開關以及2支三段開關功能。

操控多軸機航拍時，須搭配使用十動以上遙控器，具備2支兩段開關以及2支三段開關，並且具備2動撥桿微調開關功能。

2 OPTIONAL EQUIPMENT

另購商品



5,000~12,000mAh
Li-polymer Battery 6S
6S 鋰電池



Bluetooth Device
藍牙傳輸器

[HERBT001]



Clockwise x2 sets
Counter Clockwise x2 sets

7 Inch Carbon
Main Rotor x4 sets
7吋碳纖維主旋翼組 x4 sets

AERIAL PHOTOGRAPHY EQUIPMENT 航拍設備



OSD+FPV Video Transmitter
OSD+FPV 影像發射器 [HED00001]



FPV Monitor
螢幕接收器

[HEM00001]



GoPro HERO 3/4
GoPro HERO 3/4系列相機

STANDARD EQUIPMENT

標準配備

ALIGN



M470 Multicopter
M470四軸飛行機

Quick finder
零件快速購



Multicopter Canopy
機身外殼



7 Inch Main Rotor x4 Sets
7吋主旋翼組 x4 Sets



5V Step-down
Voltage Regulator
5V降壓器



APS-M Multicopter
Control Unit
APS-M多軸飛控系統



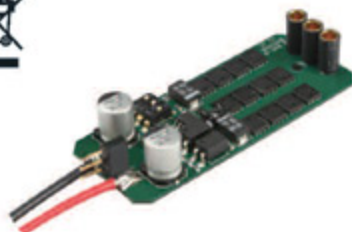
APS-M Multicopter
GPS Sensor
APS-M多軸GPS感應器



External Status LED
外掛用模式燈



RCM-BL4213(370KV)
Brushless Motor x4
RCM-BL4213(370KV)無刷馬達 x4



Multicopter Brushless
ESC x4
多軸無刷調速器 x4



PCU Power Control Unit
PCU電源控制組

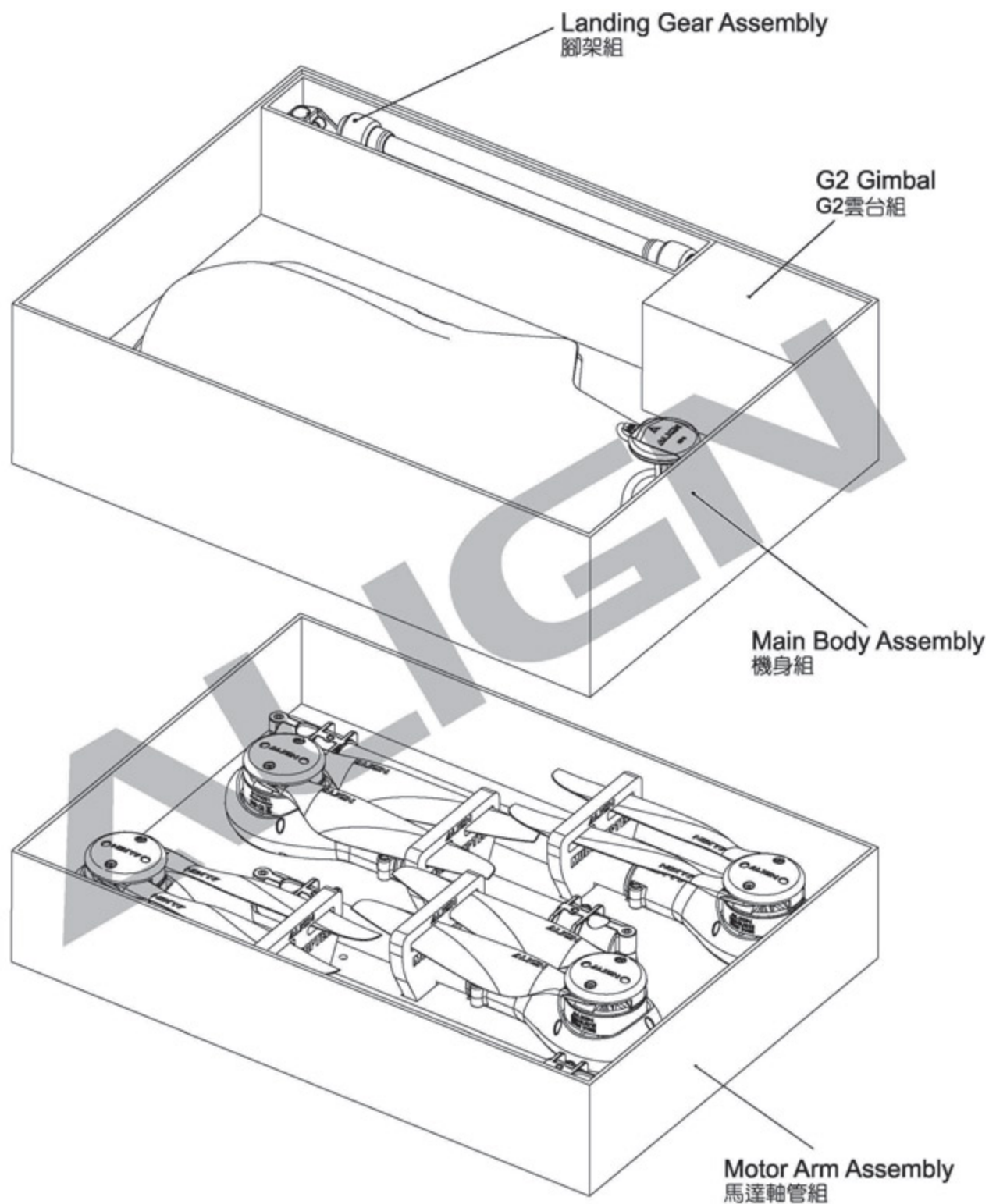


Camera not included
G2 Gimbal
G2雲台組

PACKAGE CONTENTS

包裝說明

ALIGN



ASSEMBLY SECTION

組裝說明

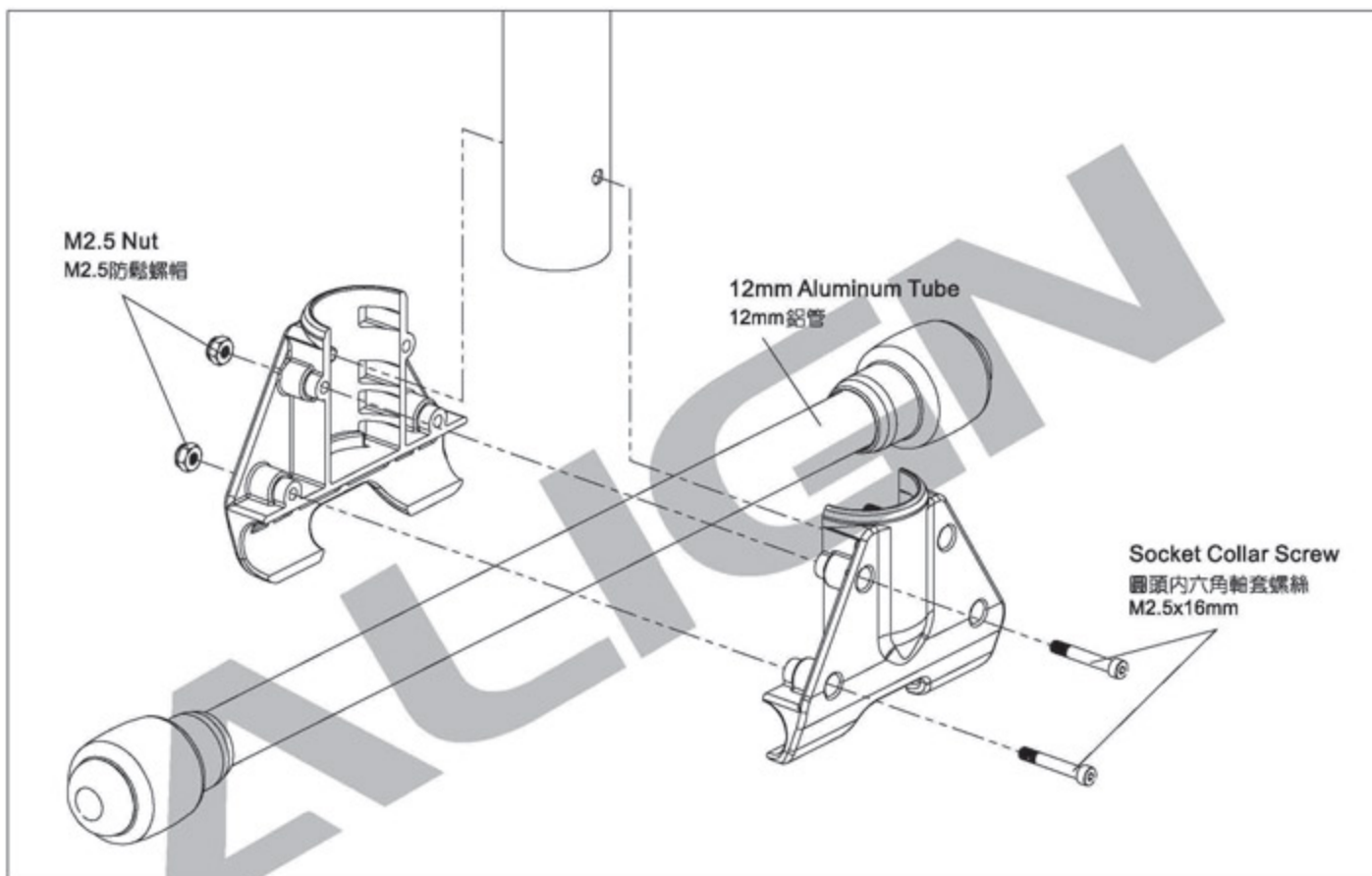
ALIGN

1 LANDING GEAR ASSEMBLY

腳架組裝

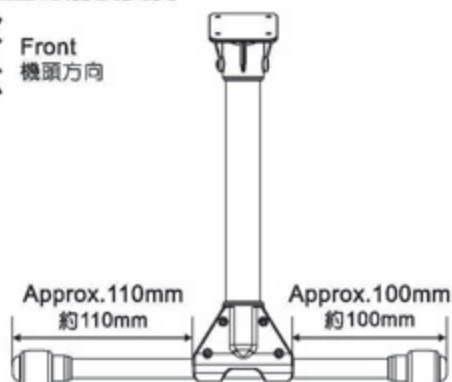
Remove landing gear assembly from box, loosen the 4 M2.5x16mm Socket Collar Screw from M2.5 nuts. Install the 12mm aluminum tube landing gear into the T mount and re-tighten the screws.

取出腳架組，先鬆開腳架T座上的圓頭內六角軸套螺絲M2.5x16mm、M2.5防鬆螺帽，將12mm鋁管鎖入腳架T座。



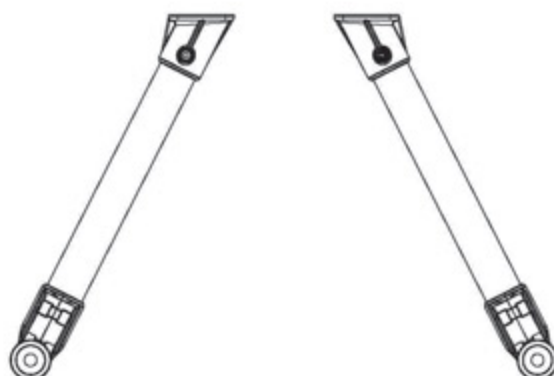
Please adjust the position of landing gear to accommodate the CG location of aircraft.

請依機身重心調整碳纖維管鎖附位置的前後長度。



Retractable Landing Gear Installation Orientation

腳架安裝方向示意圖



2

MAIN FRAME ASSEMBLY

機身組裝

1 REMOVE CANOPY

拆開機殼

Remove main frame assembly from box. Temporarily remove canopy from frame .

1. Firstly, pull on two latching sides outwards.
2. Then gently remove the canopy upward from frame.

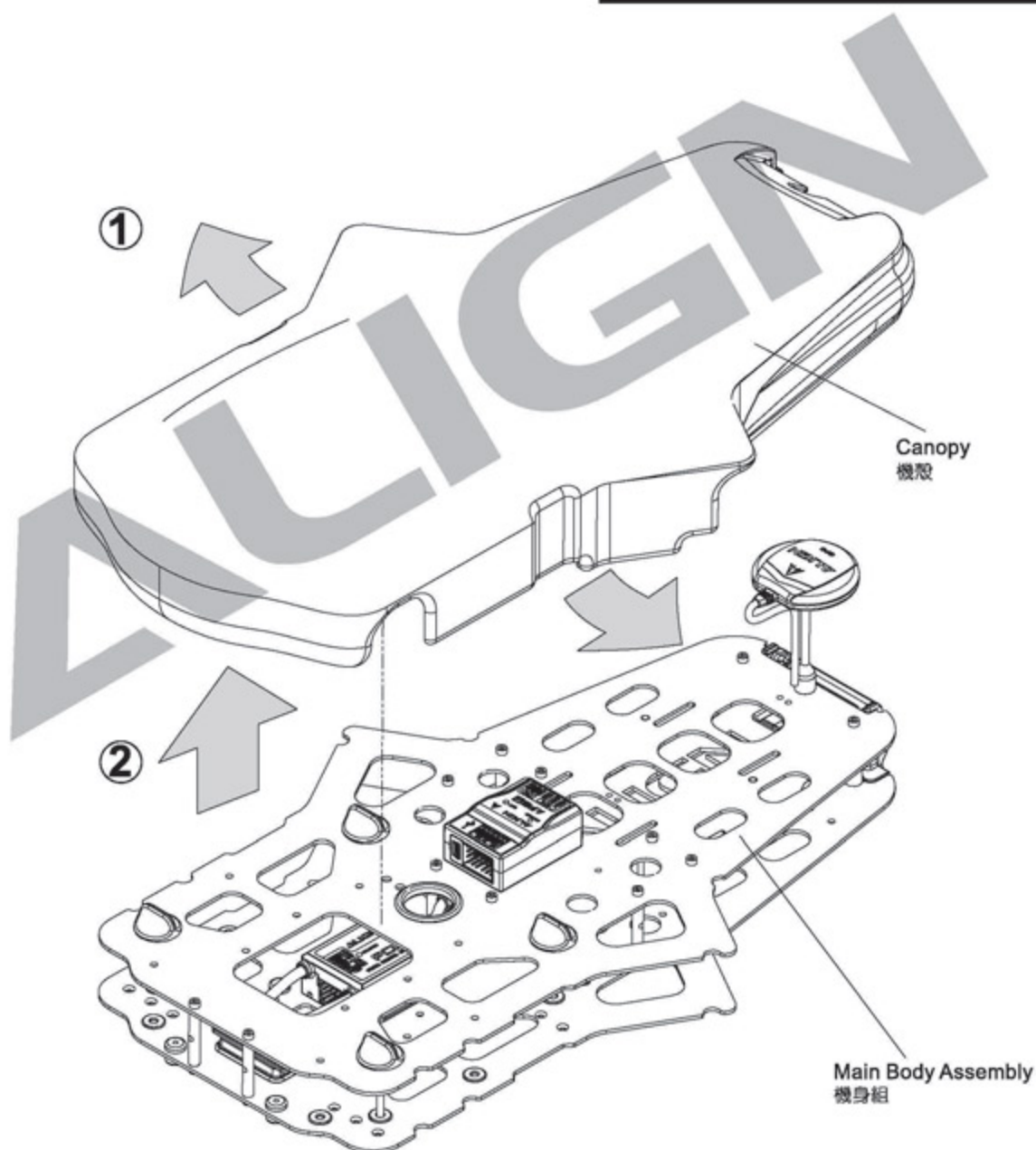
取出機身組，先將機殼拆下。

- 1.先扳開機殼側邊。
- 2.再往上提起機殼。

CAUTION
注意

Use suitable force when removing canopy. Gently pull on two latching sides outwards to remove from frame.

機殼拆卸時請使用適當力道，將機殼兩側卡槽向外側輕輕扳開取出機身，以免造成機殼破裂損壞。

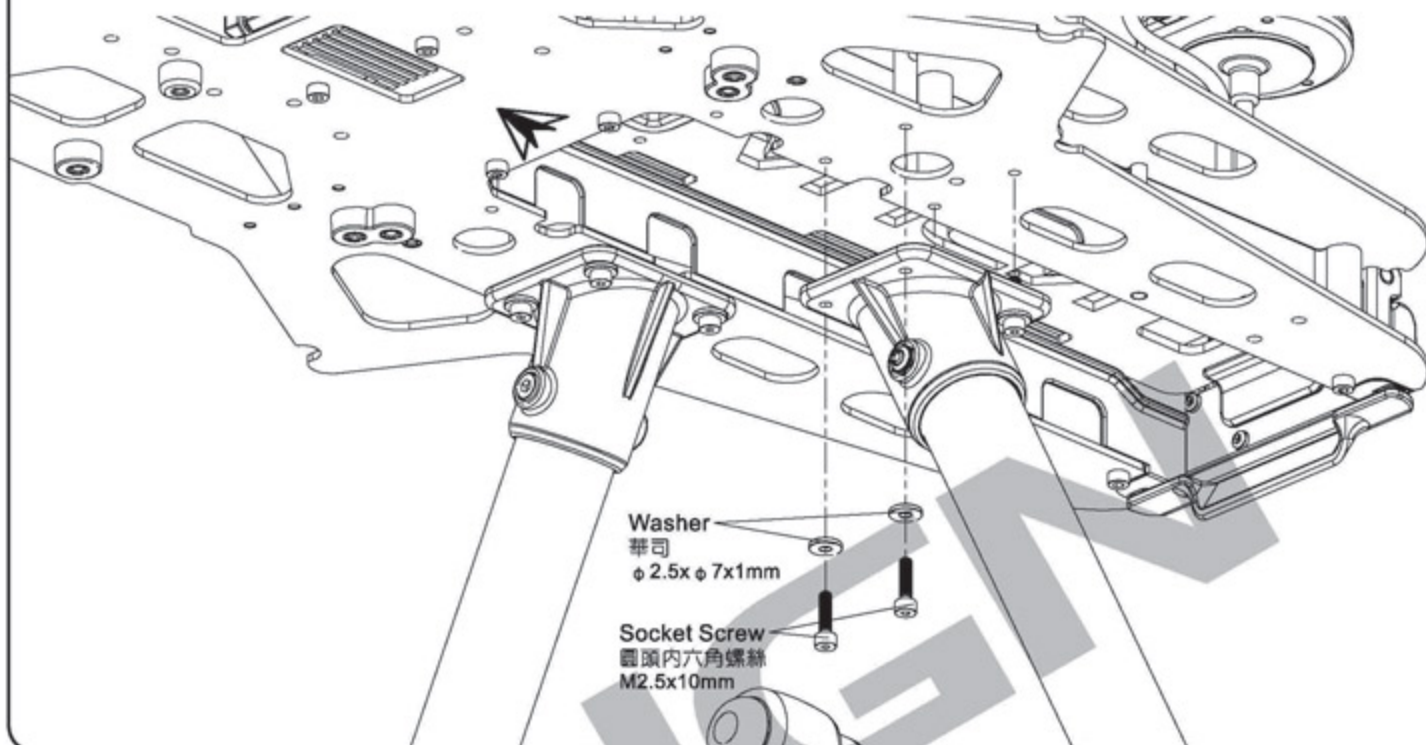


2 LANDING GEAR ASSEMBLY

腳架組組裝

Retracts can be mounted in either front or rear 4 bolts pattern based on CG. Rear is recommended for this aircraft.

M470可依配重調整腳架組固定位置，請安裝於機身後側。

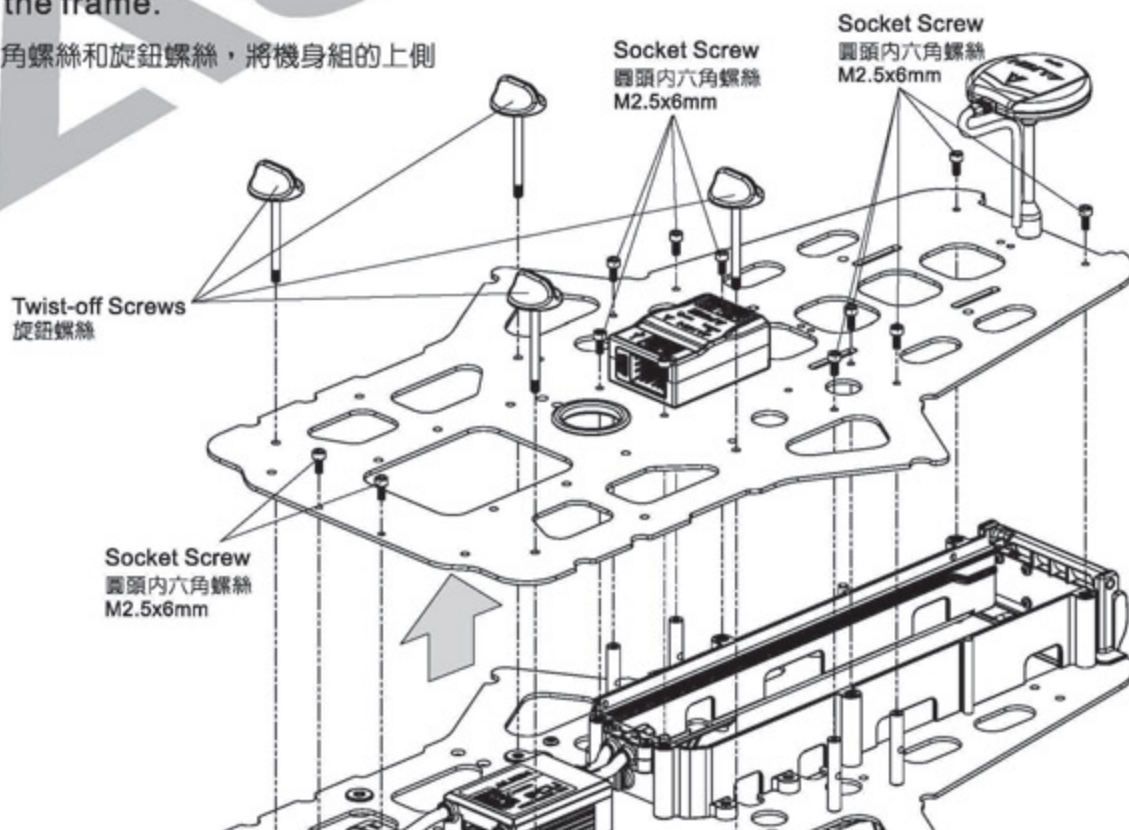


3 REMOVE TOP PLATE

拆開機身上側板

Temporarily remove all the twist-off screws and socket screws, and remove the upper plate from the frame.

鬆開圓頭內六角螺絲和旋鈕螺絲，將機身組的上側板拆開。



4 PCU POWER CONTROL UNIT WIRING DIAGRAM

PCU電源控制組接線示意圖

WARNING
警告

Any incorrect wiring or errors in electrode connection will cause electronic burn out.

訊號線誤插或極性錯誤將造成電子設備燒毀。

WARNING
警告

Make sure to install the wires with "UP" imprint facing up, and ensure the plug is inserted deep enough. Improper plug insertion may lead to poor connection or even malfunction of the APS-M unit.

插線時，請務必將刻有UP字樣端口朝上，對準插座後，確實將插頭完全插入到底，若無確實插入定位，將導致接觸不良、APS-M不動作問題產生！



APS-M Multicopter Control Unit
APS-M多軸飛控系統

OSD+FPV Video Transmitter
OSD+FPV影像發射器
[HED00001]

Optional Equipment
另購品

G2 Gimbal
G2雲台

External Status LED
外掛用模式燈

DC 5.8V Output Spare
DC 5.8V輸出 備用



Connector Label
接頭符號

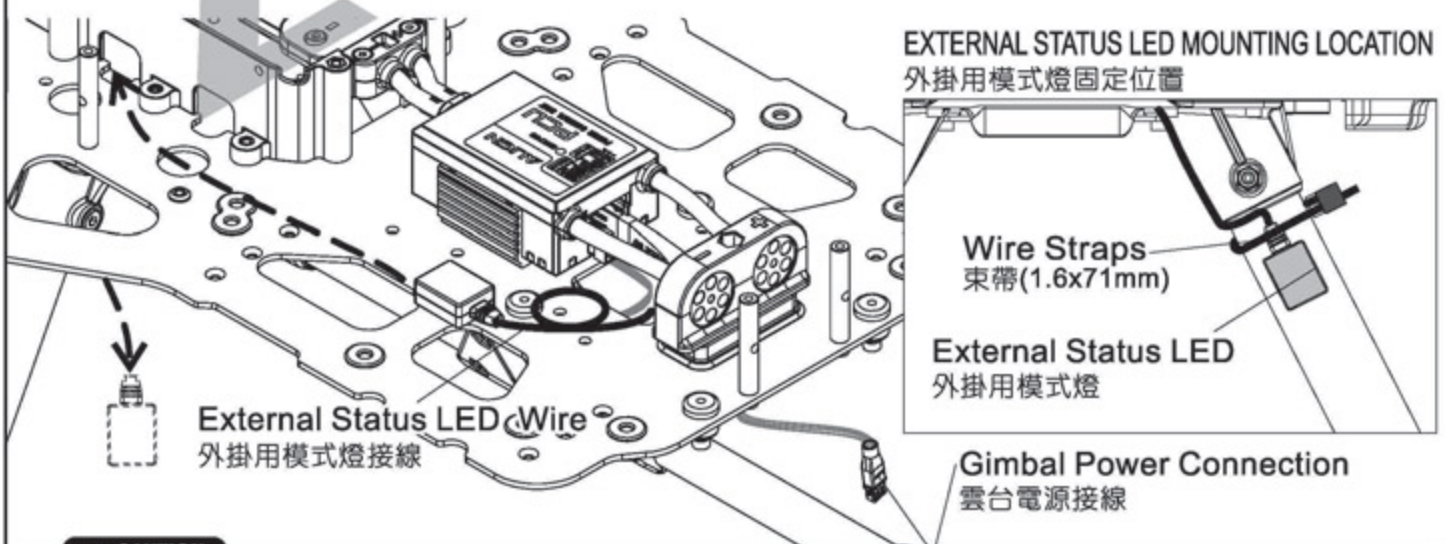


Please connect wires following correct orientation.
請依正確方向接線

EXTERNAL STATUS LED CONNECTION 外掛用模式燈接線

External status LED, thread from top down through frame plate opening along the inner side of retract, and attach to retract. Please secure LED wiring to prevent detachment during flight.

外掛用模式燈，由上往下穿過下側板孔洞，沿腳架內側，黏貼於腳架上，請使用束帶固定外掛用模式燈的接線，避免飛行時脫落。



External Status LED Wire
外掛用模式燈接線

EXTERNAL STATUS LED MOUNTING LOCATION
外掛用模式燈固定位置

Wire Straps
束帶(1.6x71mm)

External Status LED
外掛用模式燈

Gimbal Power Connection
雲台電源接線

CAUTION
注意

Please connect gimbal power wire to PCU firstly, and leave another end of the power wire for gimbal wiring.

先將雲台電源接線一端接於PCU，預留於雲台接線時用。

3

MOTOR ARM ASSEMBLY INSTALLATION

馬達軸管組組裝

1

MOTOR ROTATION DIRECTION

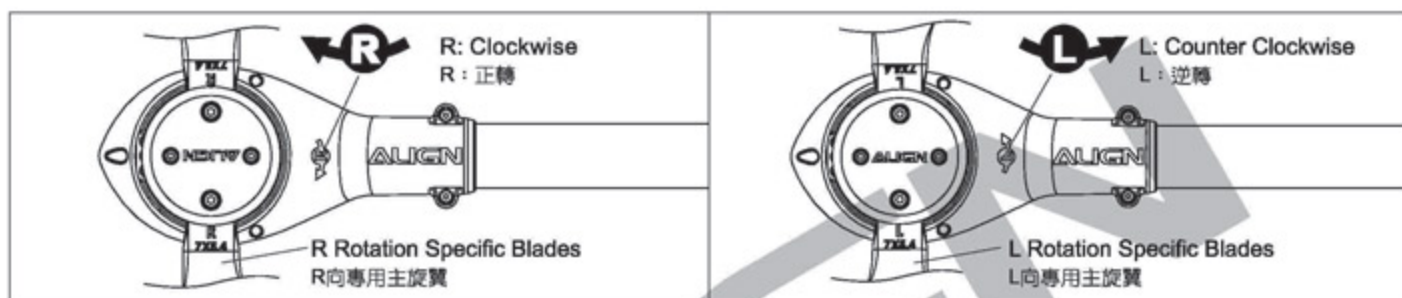
馬達正逆轉方向



注意

Identify the direction identifier on each motor mounts: R (clockwise) rotation motor must match R rotation blades; L (counter-clockwise) rotation motor must match L rotation blades.

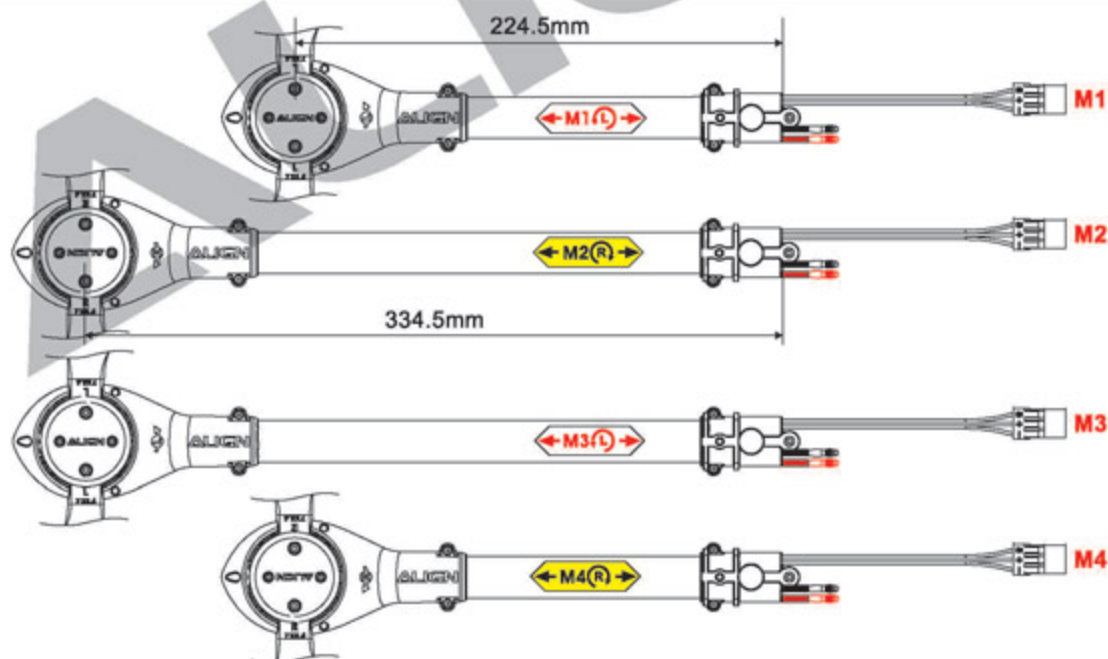
組裝前請確定馬達固定座上所標示的正、逆轉方向符號；R向馬達組必須搭配R向主旋翼；L向馬達組必須搭配L向主旋翼。



2

MOTOR ARM ASSEMBLY LENGTH

馬達軸管組前後長度



注意

Incorrect sequence of motor tube assembly or changes made to rotational directions of motor / blades may cause immediate flip-over on takeoff, and result in unforeseen dangerous situation.

馬達軸管順序組裝錯誤或自行更改馬達、主旋翼R/L轉向，將會造成機體升空後翻滾、撞毀，嚴重的將導致不可預期的意外發生。

3 MOTOR ARM ASSEMBLY INSTALLATION

馬達軸管組裝

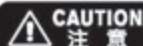
Temporarily remove the socket hex screws M3x6mm from motor arm assembly. Based on the motor direction identifier label, attach the motor tube assemblies to the correct positions on the frame.

取出軸管組時，先將圓頭內六角螺絲M3x6mm鬆開，依照馬達固定座上所標示的正、逆轉方向符號，將軸管組鎖上，固定於機身下側板的正確位置。



Insert a small screw driver into threaded sleeve to fix it in place while tightening the hex screws back.

可利用螺絲起子來固定鋁柱，將圓頭內六角螺絲鎖回。



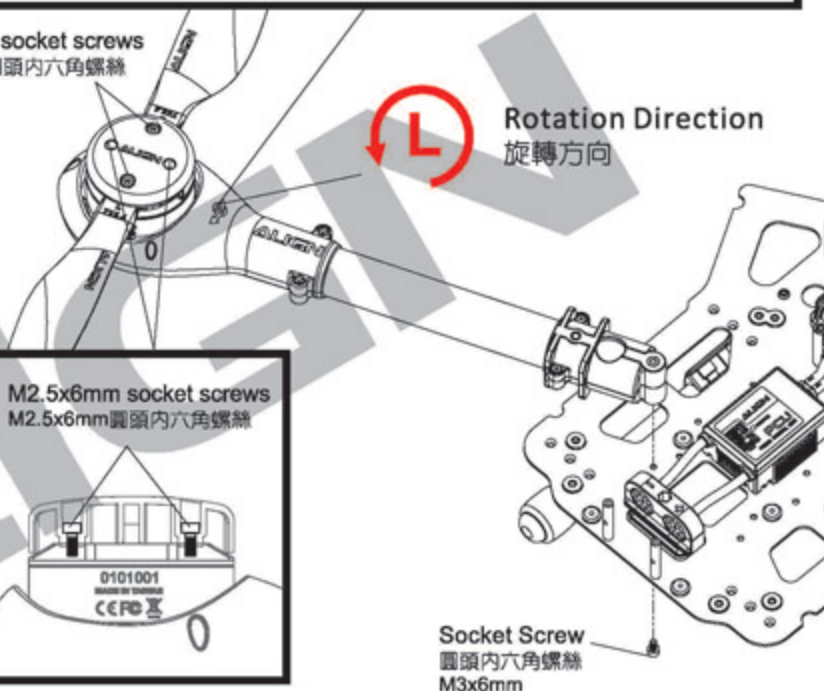
Double check the sequence and blades R/L rotation direction during motor tube assembly, ensure the install matches exactly with the instruction manual. Incorrect assembly or modifications may cause unexpected result or bodily injuries.

組裝馬達軸管時，務必再次檢查及確認，馬達組編號順序及主旋翼R/L轉向是否與說明書標示一致，錯誤或任意變動機體，將會導致不可預期嚴重的意外或人員傷害。

M3x10mm socket screws
M3x10mm圓頭內六角螺絲



Rotation Direction
旋轉方向



Use suitable force to tighten the M3x10mm and M2.5x6mm socket screws when adjusting the main rotor tightness and fixing main rotor upper cover to avoid motor winding failure.

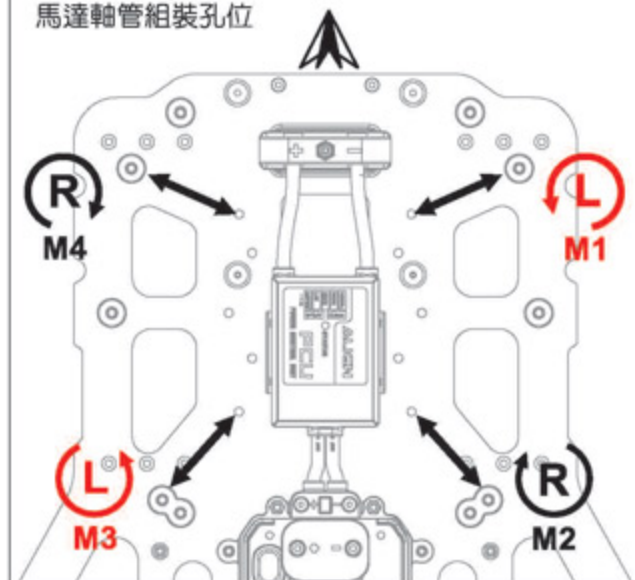
調整主旋翼緊度及固定主旋翼上蓋時，請以適當力道鎖附M3x10mm和M2.5x6mm圓頭內六角螺絲，避免鎖過緊造成馬達線圈損壞。

M2.5x6mm socket screws
M2.5x6mm圓頭內六角螺絲



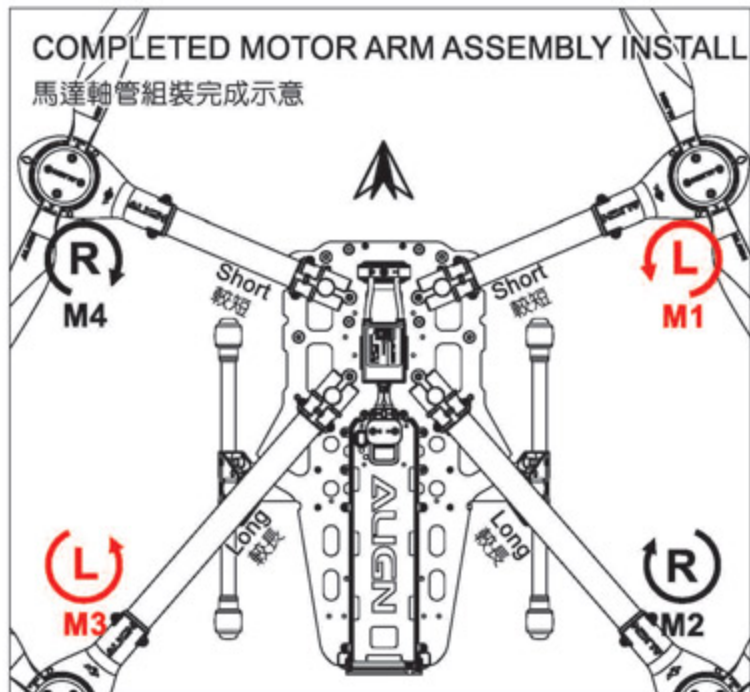
MOTOR ARM ASSEMBLY MOUNTING LOCATION

馬達軸管組裝孔位



COMPLETED MOTOR ARM ASSEMBLY INSTALL

馬達軸管組裝完成示意

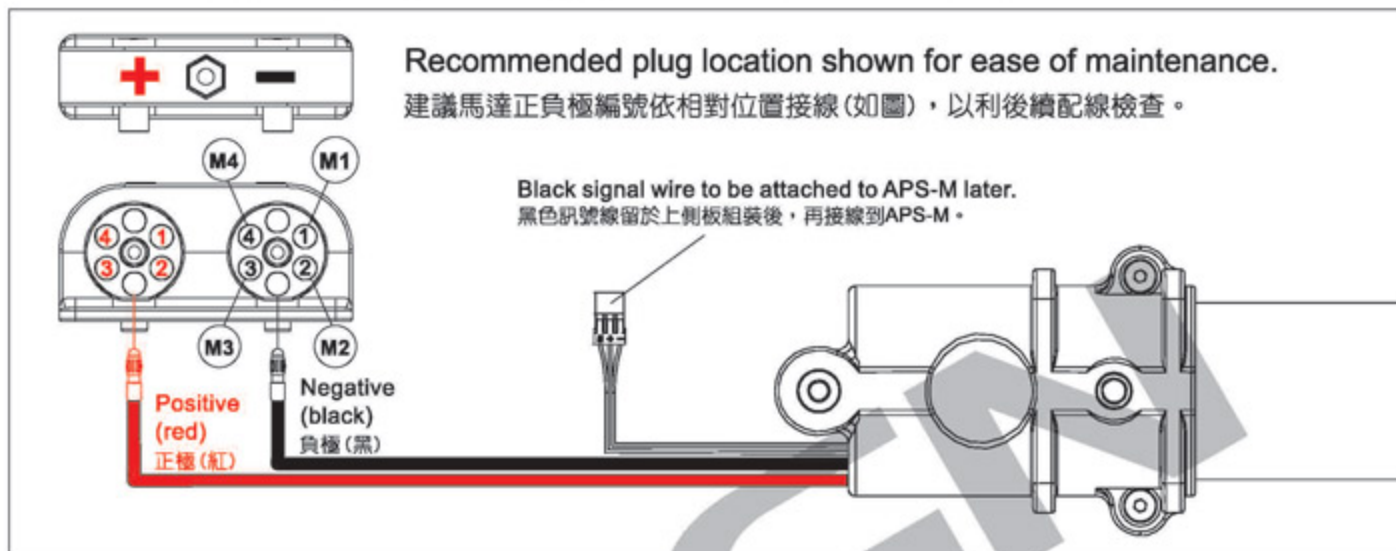


4 MOTOR ARM ASSEMBLY WIRING

馬達軸管組接線

There are 3 wires coming out of the motor arm assembly: red (+), black(-), and signal(APS-M). Connect the red(+) wire to positive power distribution cylinder, black(-) wire to negative power distribution cylinder. The signal wire will be connected to APS-M later.

每支馬達軸管組有三條出線，分別接至：紅色電源線－正極；黑色電源線－負極；黑色訊號線－APS-M。先將紅色電源線依序插入分電盤正極／黑色電源線接至分電盤負極。（黑色訊號線留於上側板組裝後再接線到APS-M）。

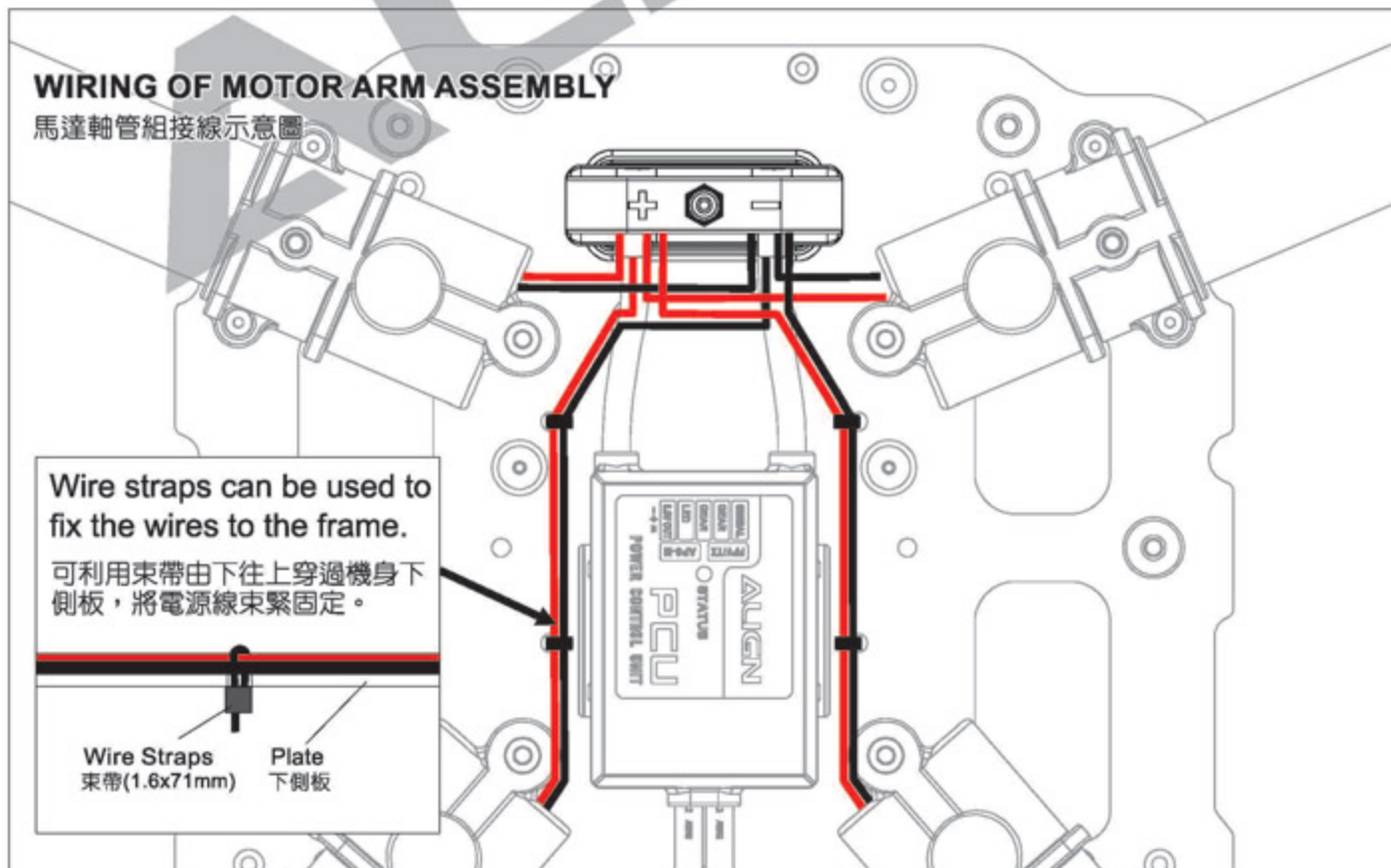


CAUTION 注意

Avoid pulling wires with excess force during wire management. Pulling the wires too hard may cause them to detach from ESC, resulting in problems with motor startup and navigation lights. 整線時請勿過度拉扯，以免ESC訊號線脫落，造成馬達啟動及飛行指示燈燈號異常。

WIRING OF MOTOR ARM ASSEMBLY

馬達軸管組接線示意圖



5 INSTALLATION OF TOP PLATE 機身上側板組裝

Route the black signal wires from motor tubes through upper plate. Re-install the upper plate using the M2.5x6mm screws removed from earlier step. Then install the M3x6mm socket screw removed earlier from motor arm assembly.

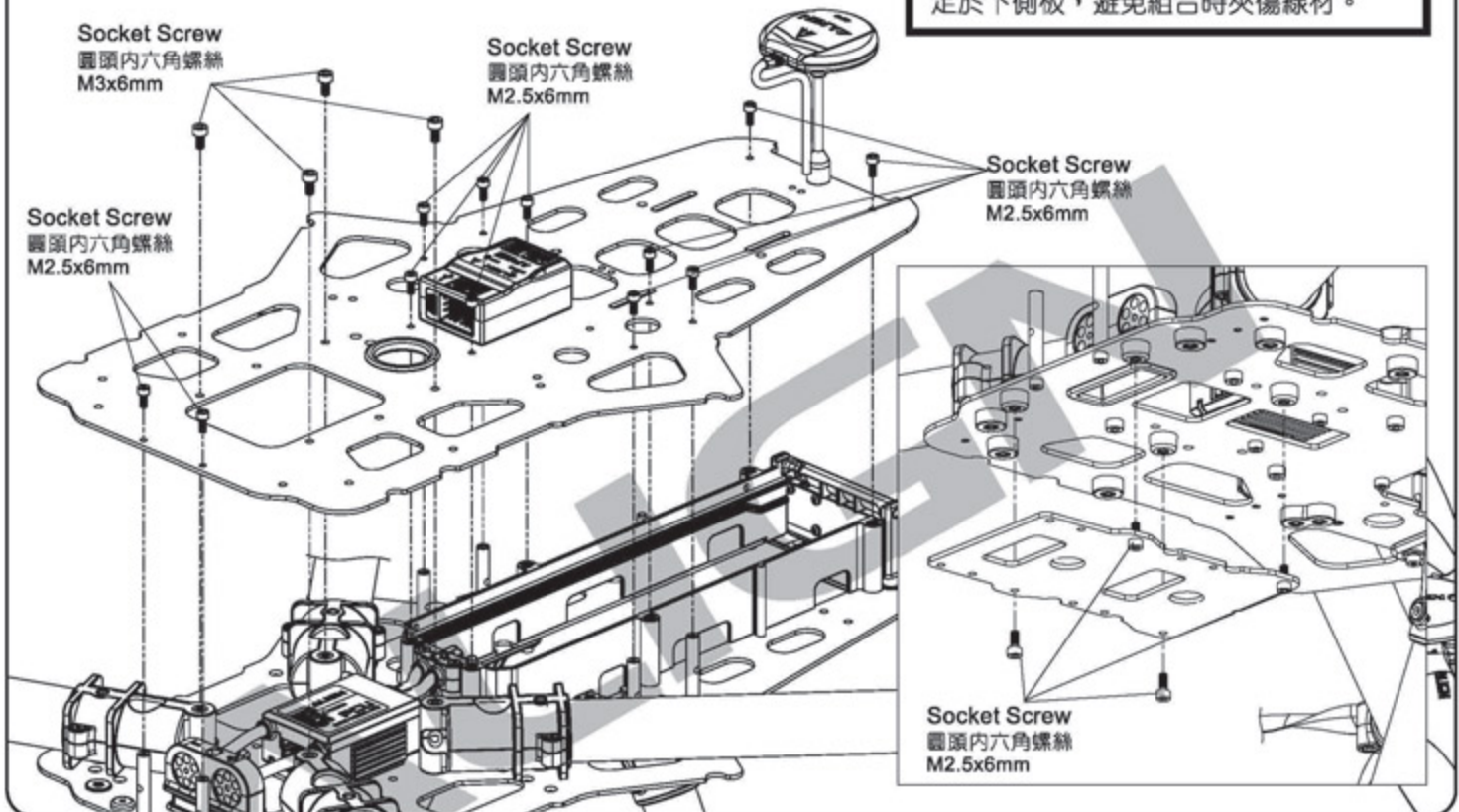
將馬達軸管中的黑色訊號線穿過機身上側板，使用原拆下的圓頭內六角螺絲M2.5x6mm將上側板鎖回機身；再以圓頭內六角螺絲M3x6mm固定軸管組。



CAUTION
注意

Prior to re-assembly, ensure upper plate can lay flat onto the frame, and that all wires are neatly tucked underneath without any pinching.

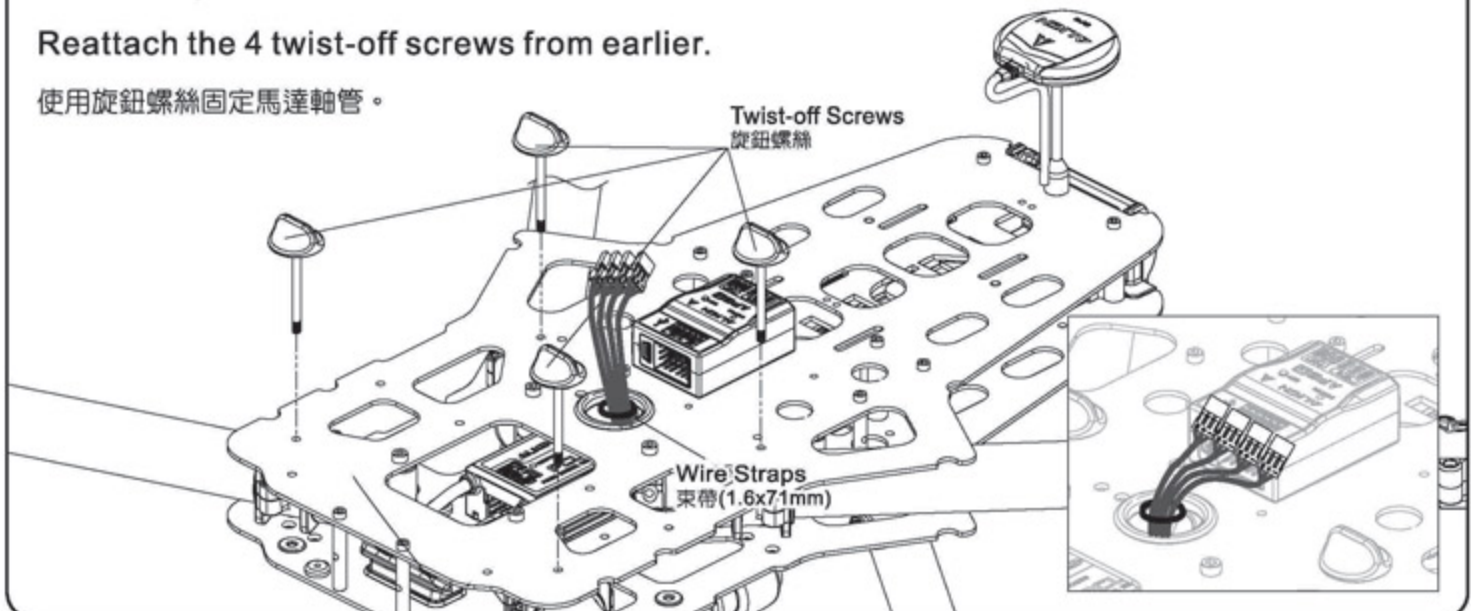
組合前，請確認上側板是否能平整置於機體組合的位置，所有線材已經整線固定於下側板，避免組合時夾傷線材。



6 SECURING THE MOTOR ARM ASSEMBLIES 馬達軸管組固定

Reattach the 4 twist-off screws from earlier.

使用旋鈕螺絲固定馬達軸管。



4

GIMBAL ASSEMBLY

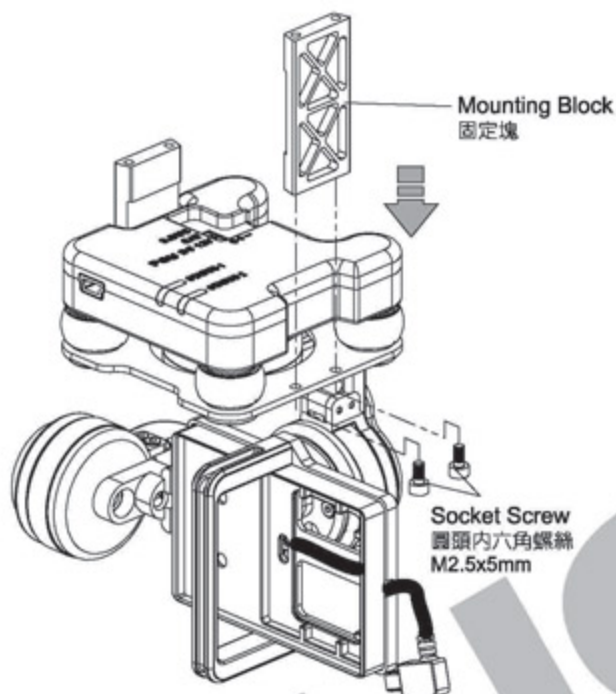
雲台組裝

1 MOUNTING BLOCK ASSEMBLY

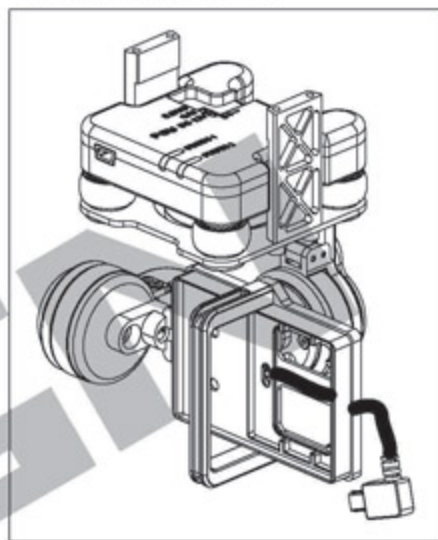
固定塊組裝

Mount the mounting block assembly to G2 gimbal using M2.5x5mm socket screws.

將固定塊使用圓頭內六角螺絲 M2.5x5mm 鎖固在 G2 雲台上。



Mounting Block Assembled
固定塊組裝完成示意圖

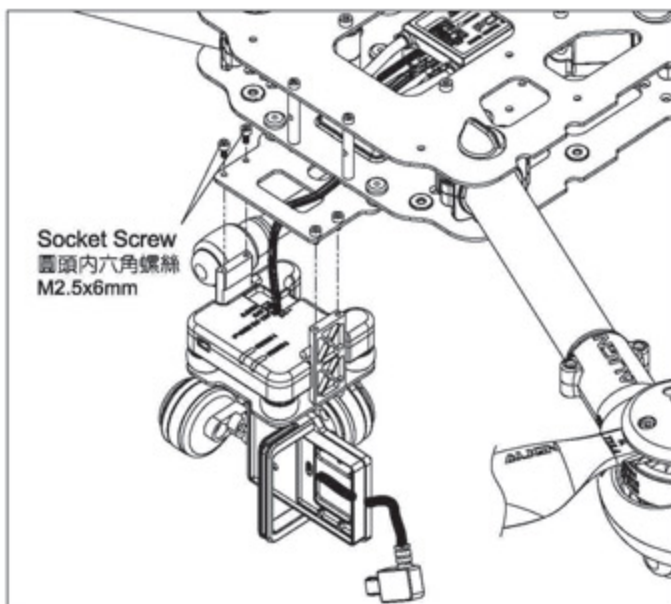
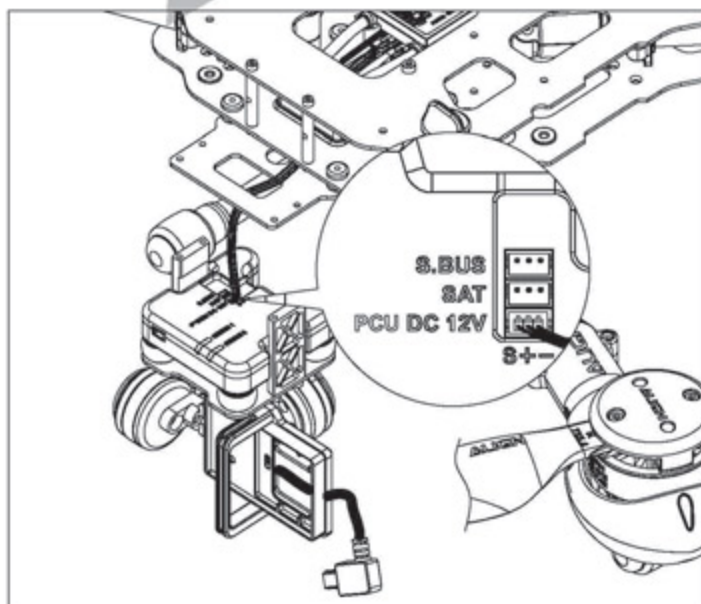


2 INSTALL THE GIMBAL ASSEMBLY ON MULTICOPTER FRAME

將雲台組裝於多軸飛行機機身

Please connect power cord to the assembled G2 gimbal, and mount it to the gimbal mounting block underneath M470 multicopter using M2.5x5mm socket screws.

請先將電源線插入組裝完成的 G2 雲台，再使用圓頭內六角螺絲 M2.5x5mm，鎖附於 M470 四軸飛行機下方的固定塊上。

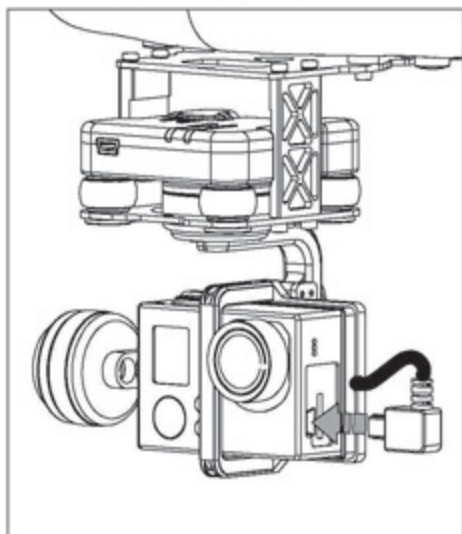
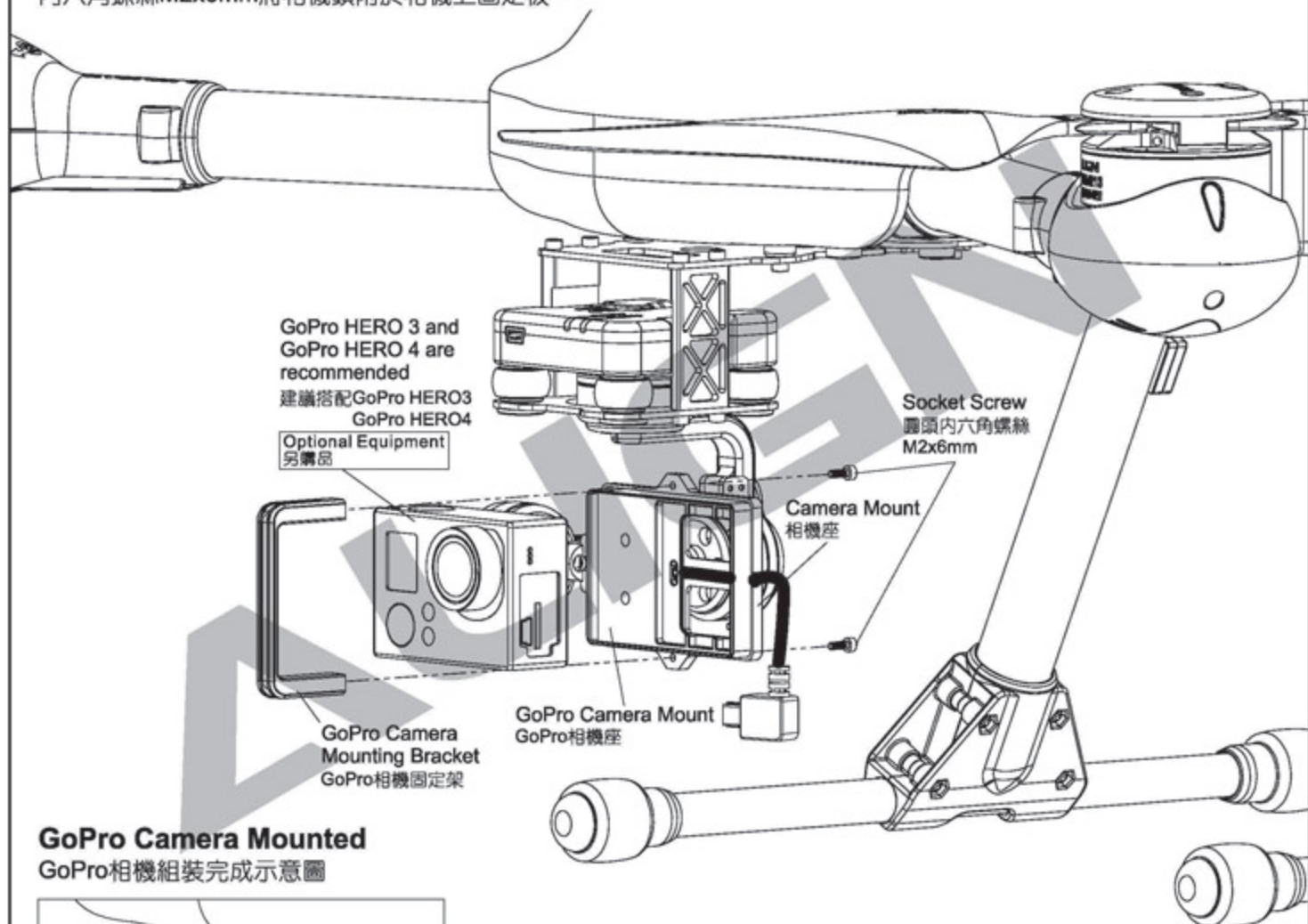


1 CAMERA POSITIONING

相機組裝

Loosen the M2x6mm socket screw behind camera mount and disassemble the mounting bracket in front. Mount the GoPro camera on camera mount using the M2x6mm socket screw.

將相機座後方圓頭內六角螺絲M2x6mm鬆開，拆開前方的相機固定架。將GoPro固定於GoPro相機座上。使用圓頭內六角螺絲M2x6mm將相機鎖附於相機上固定板。



CAUTION 注意

Once GoPro camera is mounted, double check that all parts are tightened securely to avoid loss of camera during flight.

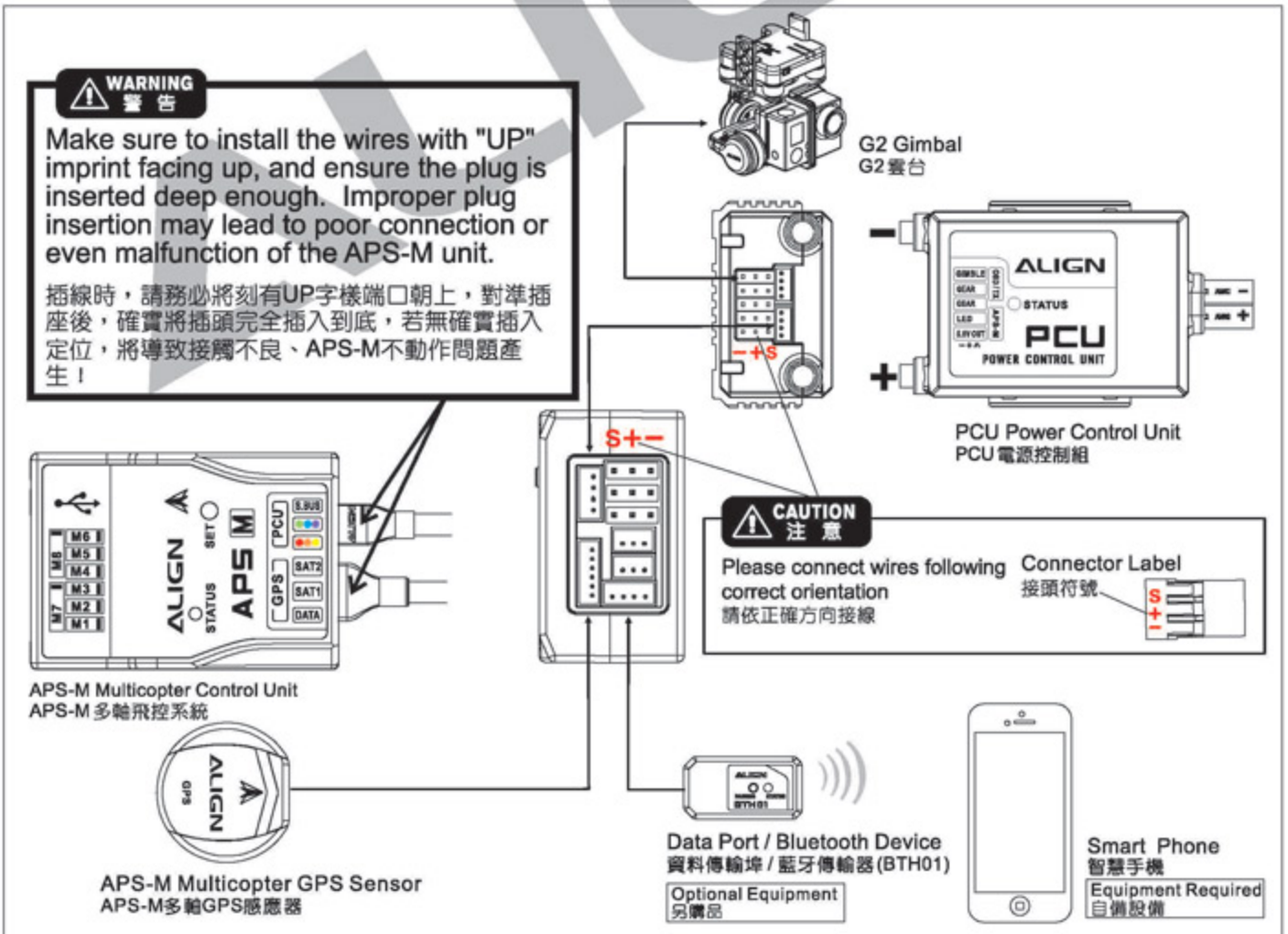
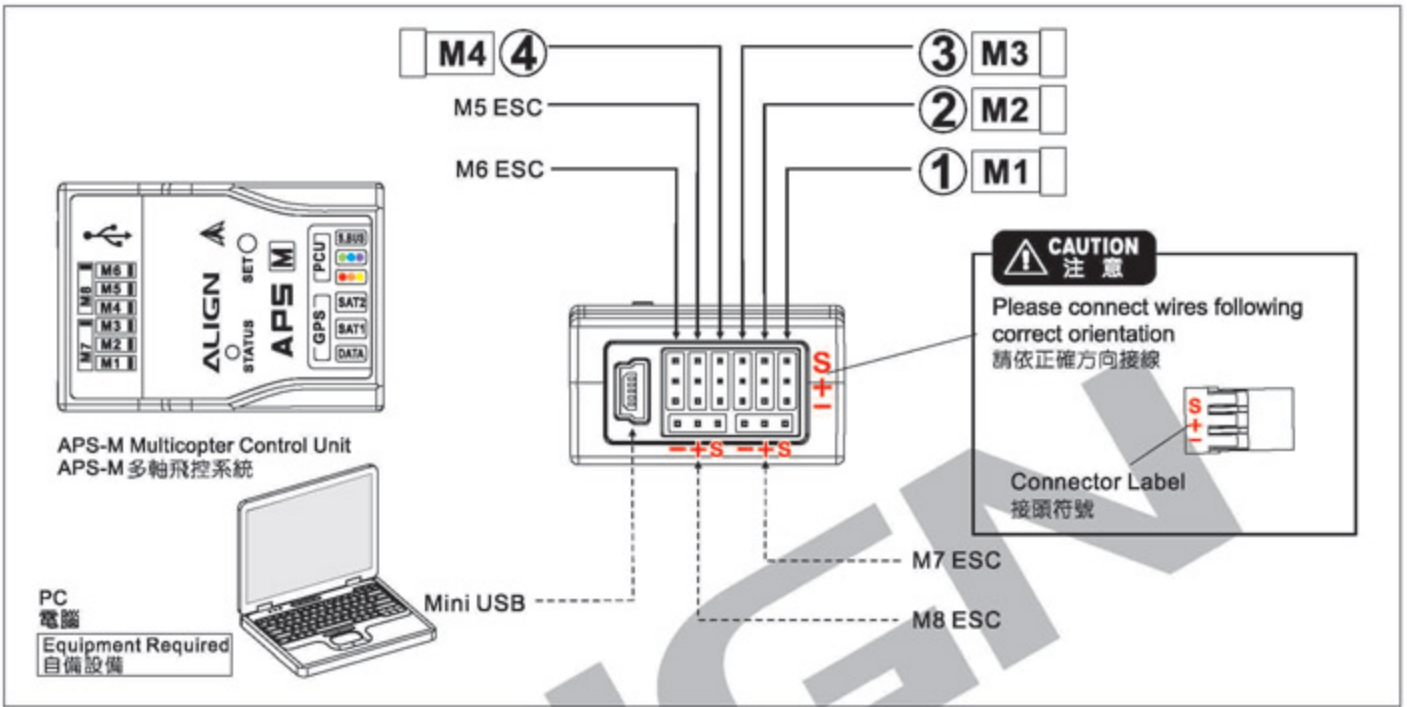
完成GoPro相機組裝後，請務必再次確認其他零件是否已鎖固完全，避免飛行時發生相機掉落損毀的可能。

6

ELECTRONICS AND GIMBAL WIRING ASSEMBLY DIAGRAM

電子設備及雲台接線組裝示意圖

1 APS-M WIRING DIAGRAM APS-M接線示意圖



APS-M AND RECEIVER WIRING METHOD

APS-M與接收器接線方式

⑤ Connect your receiver to the appropriate APS-M port as indicated.

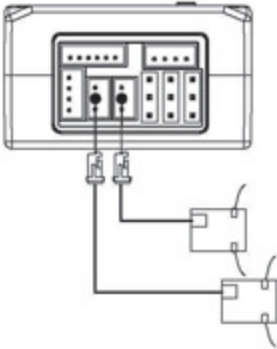
接收機接線方式，請依所使用的接收器類型接於指定孔位。

Please connect wires following correct orientation
請依正確方向接線

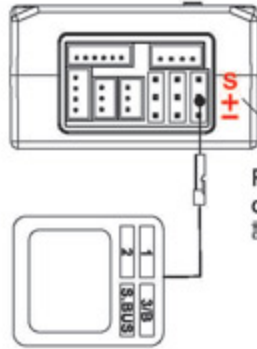
Connector Label
接頭符號



a) JR/Spektrum Satellite
JR/Spektrum 衛星天線

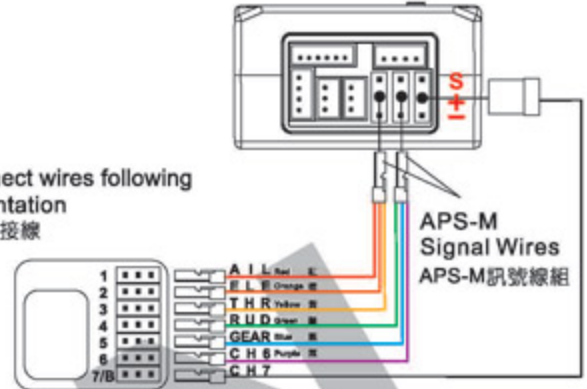


b) Futaba S.BUS/ JR X.BUS
Futaba S.BUS/ JR X.BUS



Please connect wires following correct orientation
請依正確方向接線

c) Standard Receiver
傳統接收器



APS-M Signal Wires
APS-M訊號線組

CAUTION
注意

1. When using JR X.BUS connection of DMSS satellite antennas, please select MODE A in your transmitter.

2. The standard receiver only support to Channel 7.

1. 使用JR X.BUS接線或DMSS衛星天線時，遙控器請選擇"MODE A"模式。

2. 使用傳統接收器，只支援至第7頻道。

FORBIDDEN
禁止



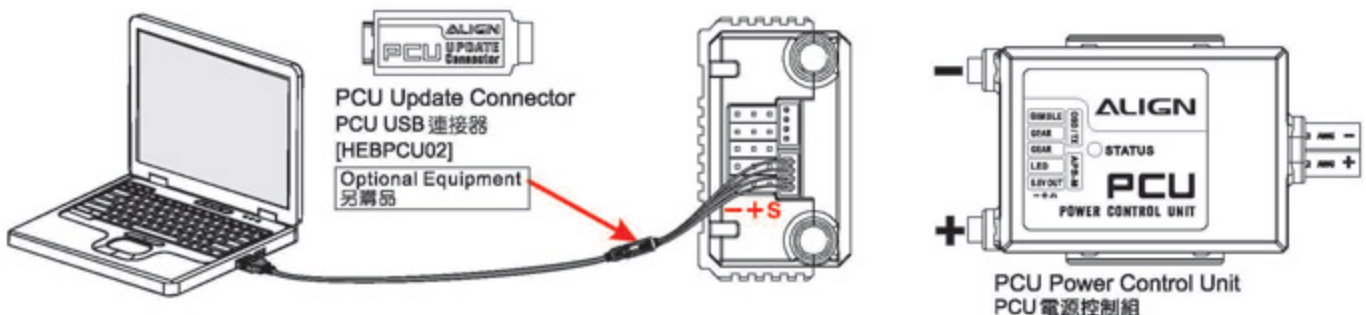
Please follow the instruction manual carefully when installing receiver. Traditional receiver channel ports are reserved specifically for the multi-colored ribbon cable. Do not directly connect standard servo plug into this port where power may be introduced into the APS-M. Doing so may cause irreversible damage to the APS-M. 安裝接收器時，請遵循說明書組裝方式接線，傳統接法的接口為彩虹線專用訊號頻道，禁止接入電源否則會造成APS-M多軸飛控系統燒毀。

2 PCU UPGRADE CABLE WIRING DIAGRAM

PCU升級更新接線示意圖

Connect the PC to PCU's APS-M port with USB adapter to perform firmware updates through PC interface program.

使用轉接線將USB接頭接到電腦端，另一端接PCU的APS-M孔位，透過電腦介面做升級更新。



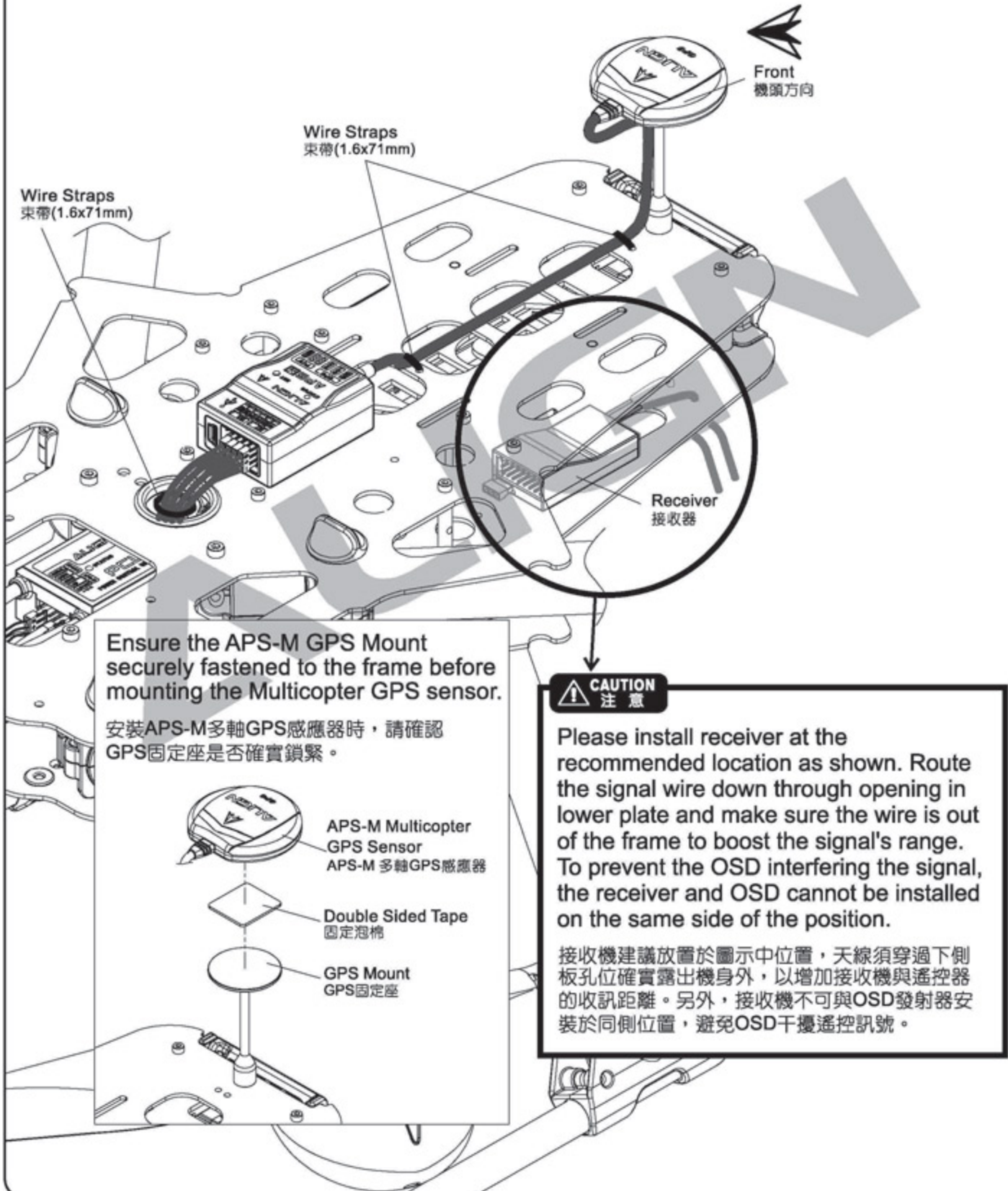
PCU Update Connector
PCU USB 連接器
[HEBPCU02]
Optional Equipment
另購品

PCU Power Control Unit
PCU 電源控制組

3 APS-M MULTICOPTER GPS SENSOR INSTALL AND APS-M WIRING APS-M多軸GPS感應器安裝及APS-M接線示意圖

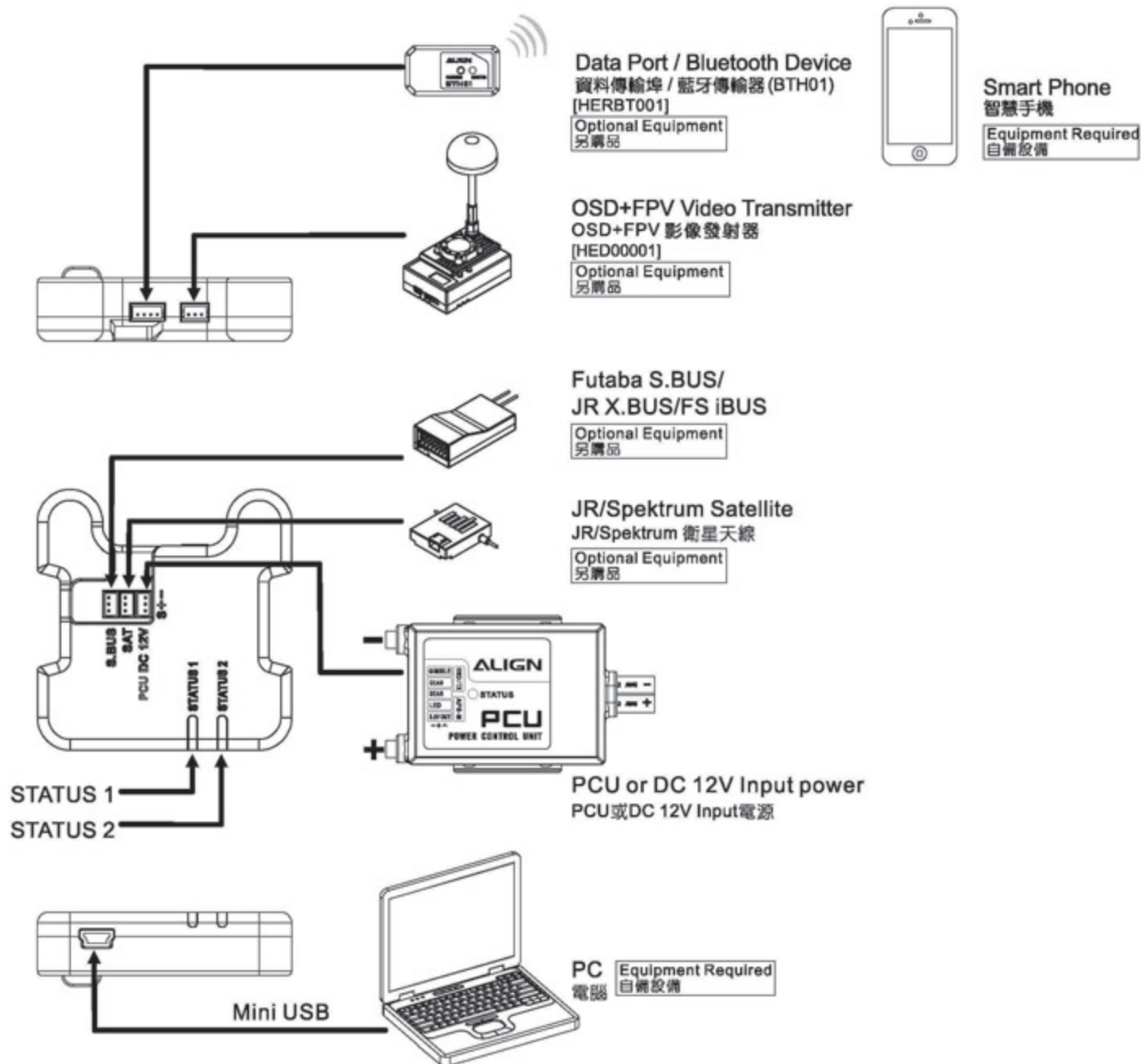
1. Install your radio receiver, and attach APS-M Multicopter GPS Sensor to GPS mount.
2. Following the label on APS-M, connect motor arm signal wires into M1~M4 ports, as well as receiver wire(s) to APS-M.

1. 安裝接收器，並將APS-M多軸GPS感應器貼附於固定架上。
2. 依面板指示位置依序①②③④將馬達軸管組訊號線，以及⑤接收機接線至APS-M。



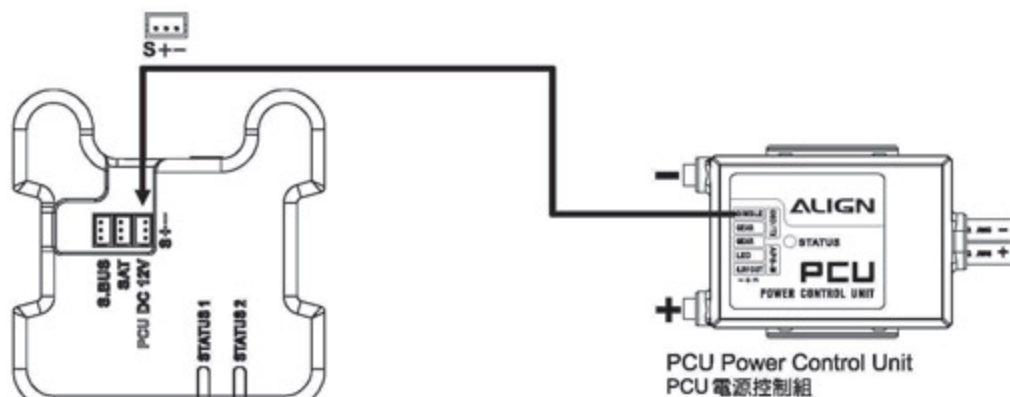
4 GIMBAL WIRING DIAGRAM

雲台接線示意圖



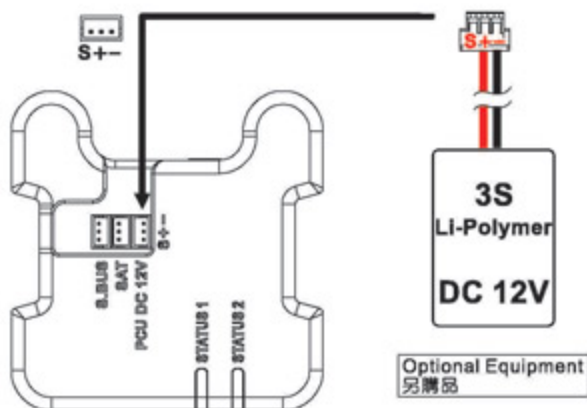
5 PCU / DV 12V INPUT WIRING DIAGRAM

PCU / DV 12V INPUT 接線示意圖



Note: Supply power by connecting the DC 12V port, when G2 gimbal operate independently without APS-M or PCU.

註：當G2雲台獨立運作（非搭載APS-M或PCU時），可從此埠輸入DC12V電源，供給G2雲台獨立運作

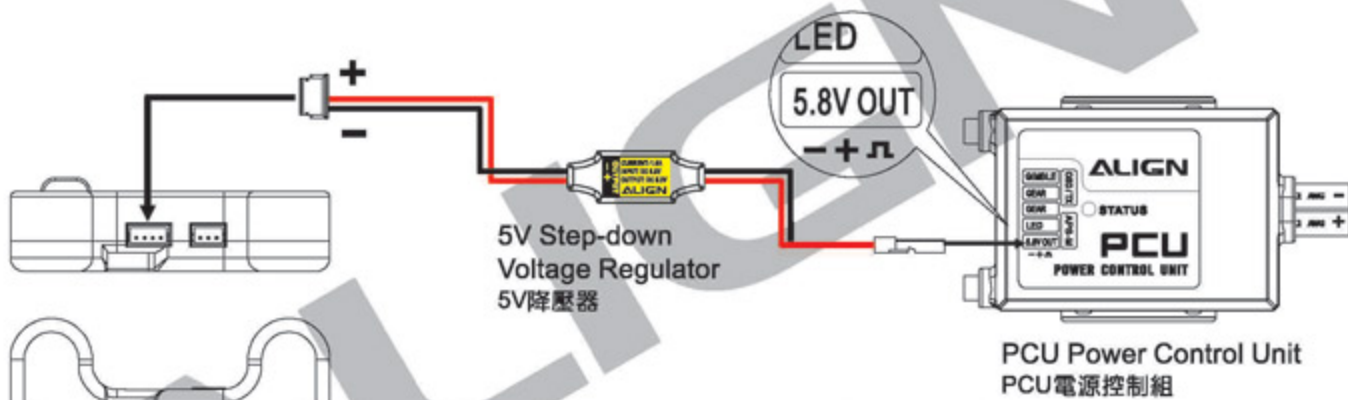


WARNING
警告

Please connect wires following correct orientation or it may cause irreversible damage to the gimbal controller's PCB.

請依正確方向接線，正負極錯誤將導致控制PC板燒毀。

6 5V STEP-DOWN VOLTAGE REGULATOR CONNECTION DIAGRAM 5V降壓器接線示意圖



WARNING
警告

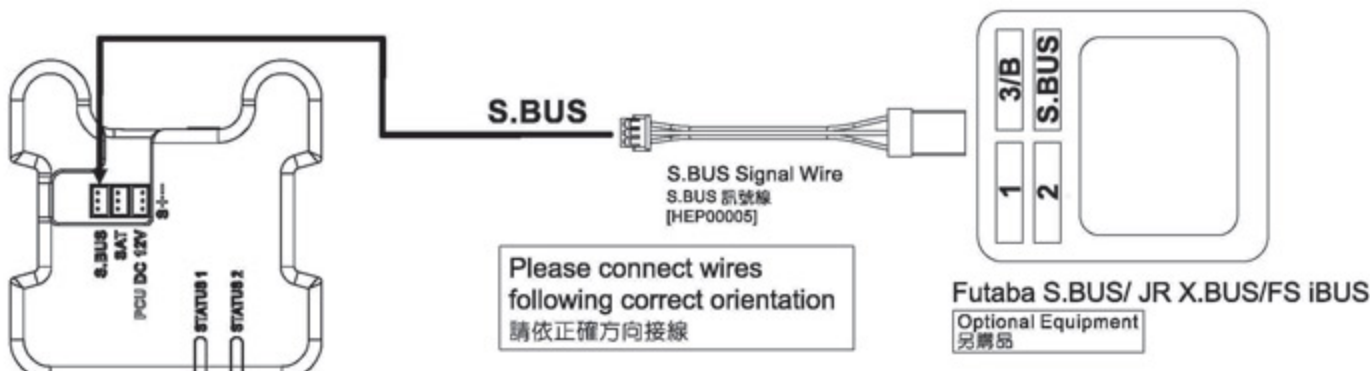
Need to be plugged into the 5.8V OUT port. Incorrect connection will lead to permanent damage of the gimbal.

端口請務必朝5.8V OUT孔位插入，接線錯誤將導致雲台燒毀。

Please connect wires following correct orientation(S,+,-) or it may cause irreversible damage to the gimbal.

安裝時，請注意接頭極性，接線錯誤將導致雲台燒毀。

7 FUTABA S-BUS / JR X.BUS/ FS iBUS WIRING DIAGRAM FUTABA S.BUS/ JR X.BUS / FS iBUS接線示意圖

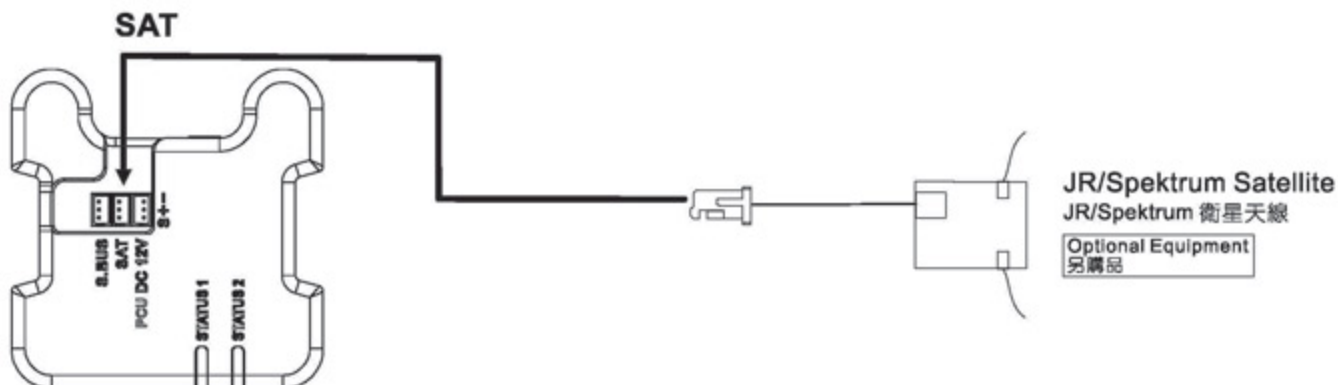


Please connect wires following correct orientation
請依正確方向接線

Futaba S.BUS/ JR X.BUS/FS iBUS
Optional Equipment
另購品

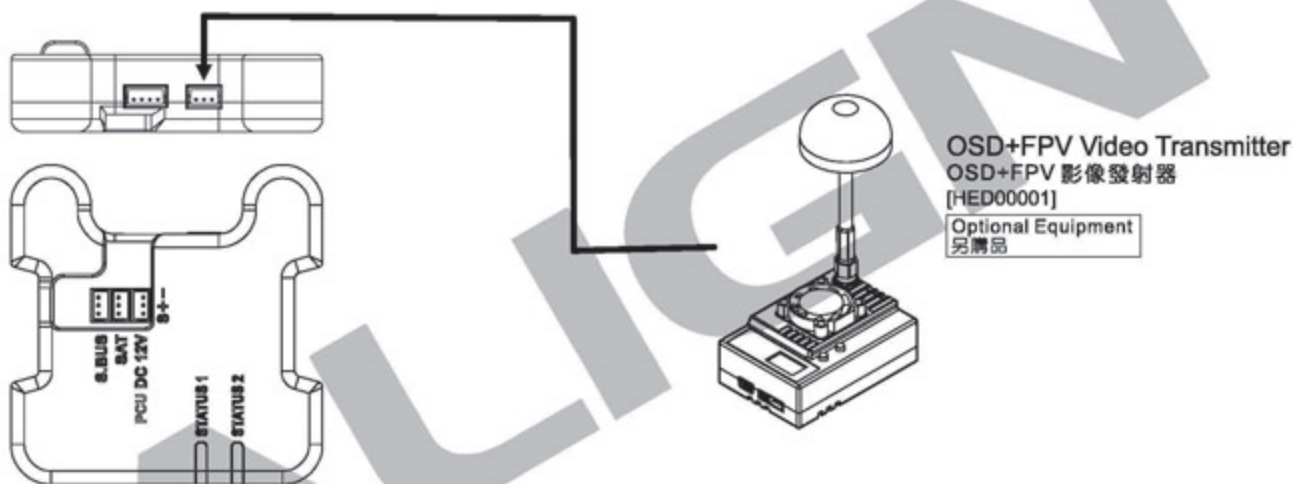
8 JR/SPEKTRUM SATELLITE ANTENNA WIRING DIAGRAM

JR/SPEKTRUM 衛星天線接線示意圖



9 OSD+FPV VIDEO TRANSMITTER WIRING DIAGRAM

OSD+FPV 影像發射器接線示意圖



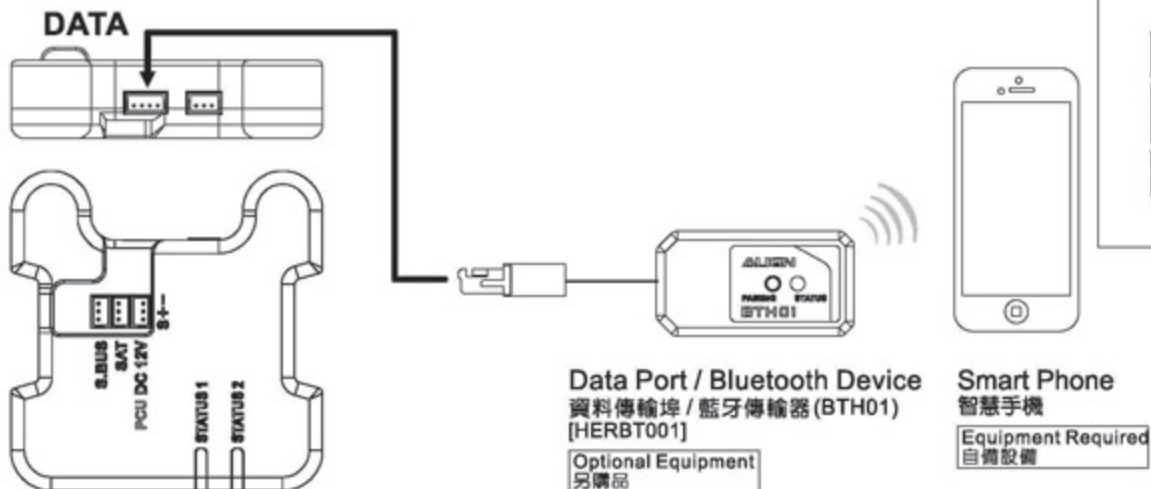
10 DATA PORT / BLUETOOTH DEVICE WIRING DIAGRAM

資料傳輸埠 / 藍牙傳輸器接線示意圖

Gimbal can be connected through smartphone App through Bluetooth Device, perform gimbal setting on various parameters.

藉由藍牙傳輸器與手機連線 Gimbal 操作介面(App)，進行雲台各項參數調整設定連接埠。

Smart Phone
Setup Interface
手機設定介面

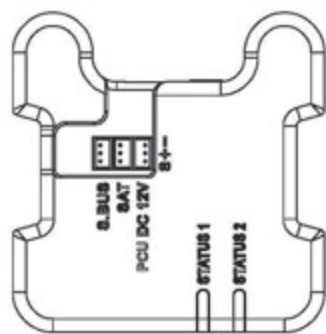


11 MINI USB WIRING DIAGRAM

MINI USB 接線示意圖

Gimbal can be connected to PC through Mini USB cable for configuration changes or firmware updates.

可利用Mini USB連結電腦，更新Gimbal主軟體或進行雲台各項參數調整設定連接埠。



PC
電腦

Equipment Required
自備設備

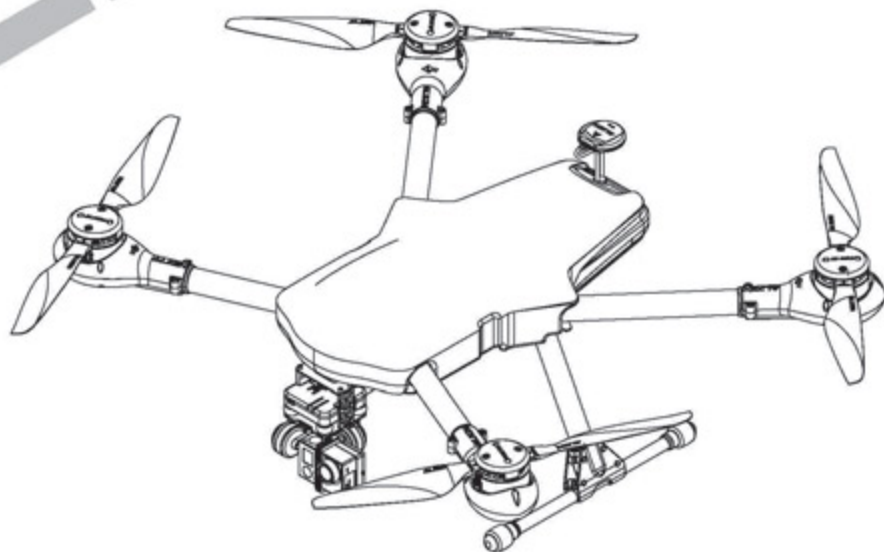
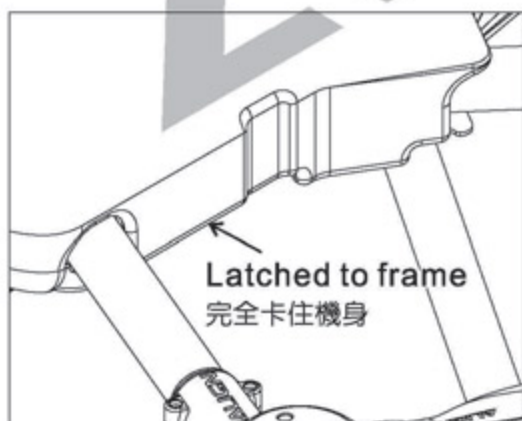
Mini USB

12 CANOPY INSTALLATION

機殼組裝

Re-attach canopy to complete installation.

將機殼裝於機身即完成組裝。



注意

Ensure canopy is latched to the lower frame plate to prevent accidental separation during flight.

機殼裝上機身時，請務必確認機殼完全卡住機身下側板，避免飛行時脫落，而導致不可預期的意外。



注意

Canopy must be installed to avoid turbulence disturbance and ensure optimal flight performance.

飛行時必須蓋上機殼，以確保飛行機不受氣流干擾達到最佳的飛行效能。

4

BATTERY INSTALLATION ILLUSTRATION

電池安裝示意圖

Double-decker battery plate design for a single 6S 22.2V 12,000mAh (or less) battery (physical dimension permitting), or two batteries with 8,000mAh or less capacity. Battery selection is flexible, and can be used to adjust the CG location of aircraft. Battery plate feature patented anti-spark design, effectively minimize sparks during connection of battery, lowering problems such as damages to electronics and poor connection due to premature connector wear.

雙層設計的電池板，可選用單層電池使用，一顆6S 22.2V 12,000mAh以內；或是使用雙層電池板同時安裝兩顆8,000mAh容量以內電池，電池可彈性選擇使用與調整機體重心。電池板內搭載新型“防火花”專利設計，能有效防止電池快拆插入時所產生的火花，降低電子設備傷害及接頭耗損接觸不良問題。

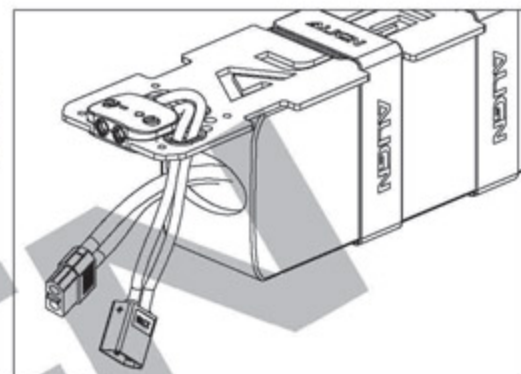
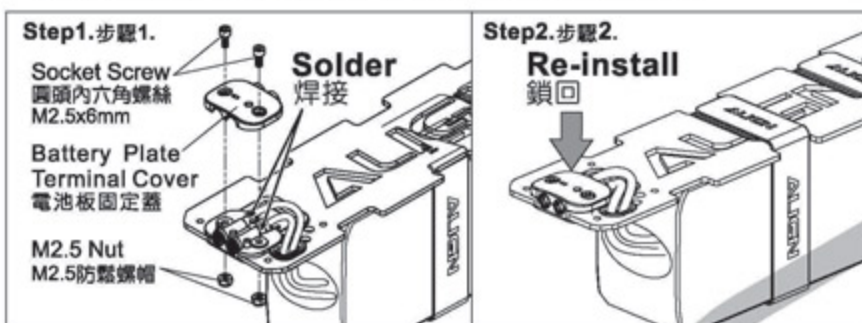
1. FIXED BATTERY WIRING METHOD 電池固定式接線方式

Loosen battery plate terminal cover, solder the wires to the corresponding + - terminal, and re-install the battery plate terminal cover.

先鬆開電池板固定蓋，將電池電源線依+-指示焊接於接頭上再鎖回。

2. PLUG TO BATTERY WIRING METHOD 電池插頭接線方式

電池插頭接線方式



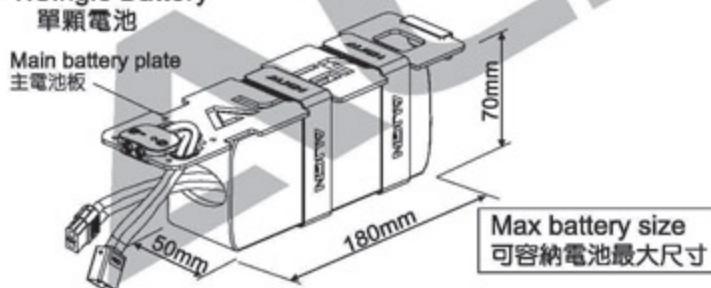
3. BATTERY INSTALL EXAMPLE FOR M470

M470電池使用示意圖

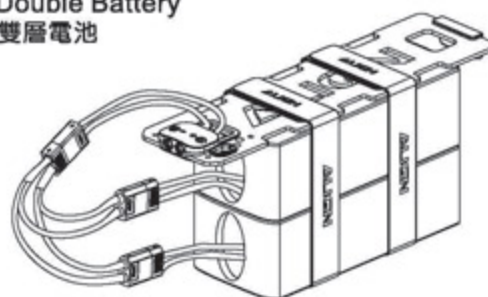
M470 with gimbal is suggested to fly using a single 5,200mAh (or more) battery, or two batteries with 5,200mAh to match perfect CG balance and reach longer flight time.

M470可使用單顆5,200mAh以上的電池，或是2顆5,200mAh電池重疊並聯使用，讓M470有更長的飛行時間。

3-1. Single Battery 單顆電池



3-2. Double Battery 雙層電池

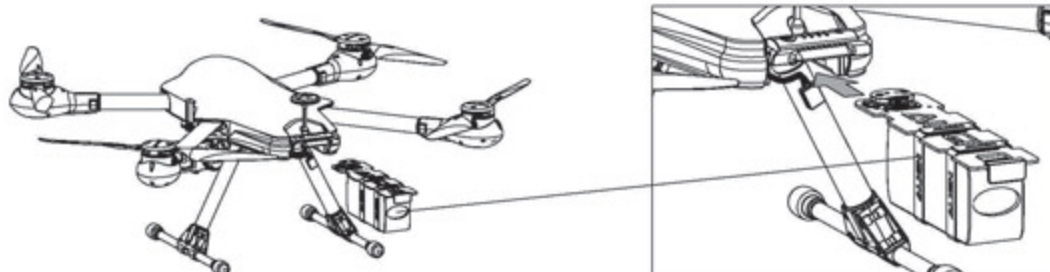


4. M470 BATTERY INSTALLATION ILLUSTRATION

M470電池安裝示意圖

Lift open the multi-function battery hatch. With battery securely strapped to battery mounting plate, slide the whole plate assembly into the rail, push all the way in until a latching sound is heard. Then close the multi-function battery hatch.

先將多功能電池蓋掀開，把固定好電池的電池板順著滑軌推入，確認發出“喀答”聲響完全裝入，再將電池蓋蓋回。



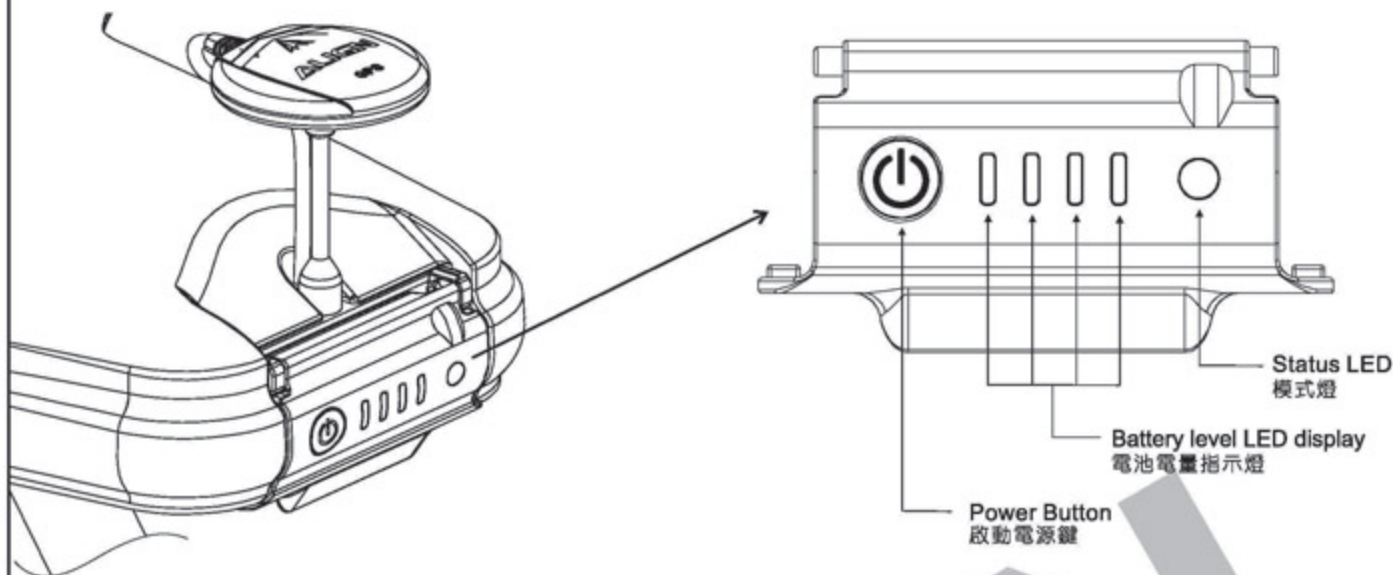
For optimal balance on the M470, mount the battery on the main battery plate.

M470電池請安裝於主電池板位置，以達到最佳配重效果。

5

INTELLIGENT POWER MANAGEMENT

智慧型電源控制系統



POWER ON 電源開啟

Battery level check: Momentary press of power button to check remaining power.

Power On: Press and hold power button for 3 seconds until battery indicator LEDs light up and Status LEDs flash.

Power Off: Press and hold power button for 3 seconds until all LEDs shut off.

檢查電量：短按電源鍵檢視剩餘電量。

開啟電源：長按電源鍵3秒，電池電量指示燈亮起與模式燈閃爍，即完成開機動作。

關閉電源：長按電源鍵3秒，所有燈號熄滅，即完成關機動作。

BATTERY LEVEL INDICATOR DESCRIPTION 電池電量指示燈說明

Battery level LED display 電池燈號顯示	Battery level indicator 電量顯示
	75%~100%
	50%~75%
	25%~50%
	0%~25%

AUTOMATIC POWER SHUT-OFF 智慧型電源自動關閉

Align's Power Control Unit (PCU), has intelligent power hibernation function where the multicopter will power down automatically minutes after landing. The default hibernation time is 10 minutes, but can be adjusted according to actual needs. Please refer to page 31 for setting instruction.

亞拓PCU電源管理系統，具備智慧電源管理功能，當多軸機降落閒置時，會執行電源關閉保護。自動關閉時間原廠預設值為10分鐘，您可以依實際需求設定關機時間。設定方式請參考第31頁。

6 FLIGHT NAVIGATION LIGHTS

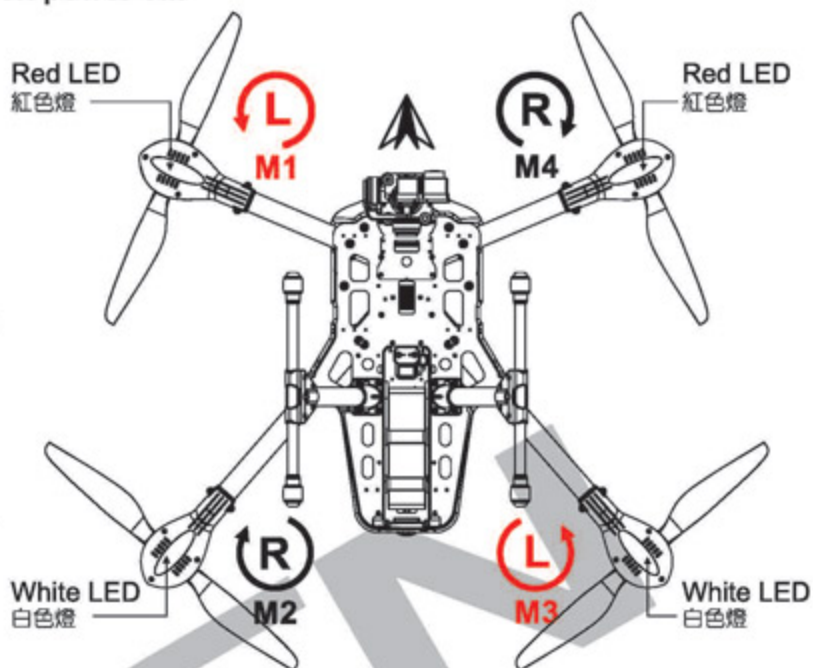
飛行指示燈

1. Flight navigation lights will light up when power on.
2. Flight navigation lights will shut off when power off.

1. 多軸機開機後指示燈隨之全部開啟。
2. 多軸機關機後指示燈隨之全部關閉。



Do not operate R/C aircraft if the flight navigation lights exhibit abnormal behavior during power up.
飛行指示燈開啟異常禁止飛行。



7 COLLAPSIBLE MOTOR ARMS

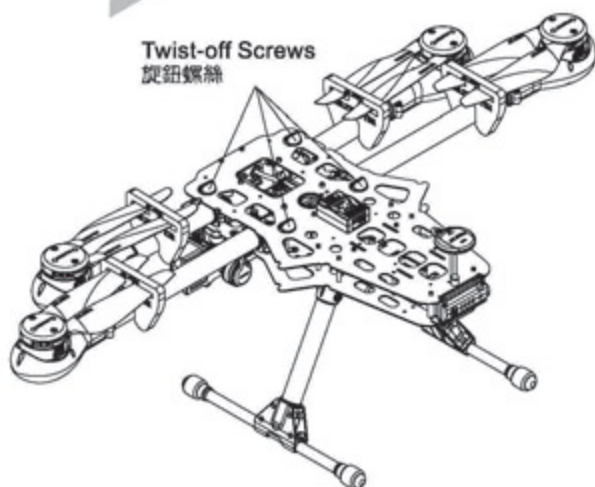
馬達軸管收納示意圖

The motor arm assemblies feature foldable design. Simply loosen the twist-off screws for the arms to swivel, reducing the footprint for ease of transport.

多軸飛行機軸管可快速收折設計，只要以手轉開旋鈕螺絲，就能輕鬆收折馬達軸管，調整軸管位置，減小體積方便攜帶，輕鬆收納不佔空間。

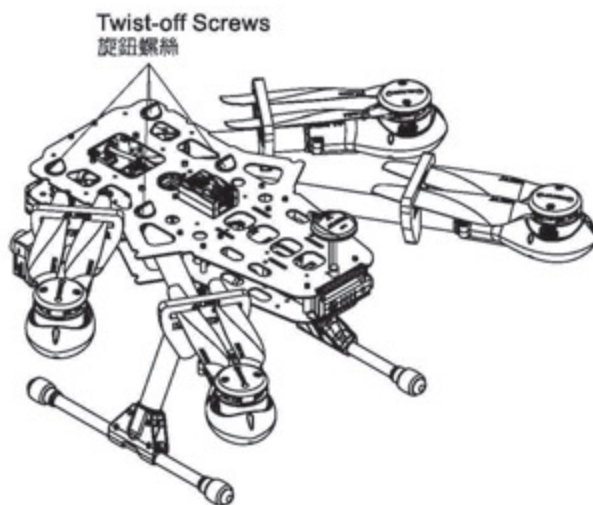
MOTOR ARMS FOLD TOWARD THE SIDES

馬達軸管往旁邊兩側收折示意圖



MOTOR ARMS FOLD TOWARD THE REAR

馬達軸管往後側收折示意圖



APS-M FEATURES

APS-M產品特色

ALIGN

Brand new APS-M Multicopter Control Unit with superior performance through cutting edge information technologies, utilizing high precision sensors and modern system control subroutines. Support quad(4), hex(6), and octo(8) rotors. Flight modes include attitude, GPS velocity, GPS angular, intelligent, and manual. In addition, it features failsafe auto return home, low voltage failsafe (through LED indicator and auto Return Home), OSD signal output, gimbal control, and Point of Interest (POI) function.

全新的APS-M多軸飛控系統，尖端IT工業創造出卓越性能，採用高精度感應元件與先進的演算法程式控制，發揮出高穩定性、多功能、高可靠度的性能。支援四軸、六軸與八軸多軸機、具備多種飛行模式（姿態、GPS速度、GPS角度、智能、手動）、自動返航與失控保護自動返航、低電壓保護（閃燈警示與自動返航）、OSD訊號輸出、雲台控制、定點環繞等功能。



Supports 6 multicopter configurations: 4 rotors +, 4 rotors X, 6 rotors +, 6 rotors X, 8 rotors +, 8 rotors X.

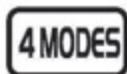
支援6種多軸飛行機，四軸+型、四軸X型、六軸+型、六軸X型、八軸+型、八軸X型



GPS

Build in APS-M Multicopter GPS Sensor for precise location fixing function.

內建APS-M多軸GPS感應器，提供精準的定位功能。



4 MODES

Multiple flight modes including manual mode, attitude mode, GPS Angular mode, and GPS Velocity mode.

提供手動模式、姿態模式、GPS角度模式、GPS速度模式，可滿足玩家使用需求。



Equipped with automatic return home function with remote activation ability from R/C transmitter. When RC transmitter signal is lost, multicopter will automatically fly back to home position.

具備自動返航，可由遙控器開關開啟返航；當失去遙控器訊號，飛行機會自動飛回Home點。



Features two stage battery low voltage protection system; Stage 1 provides visual warning through flashing LEDs, stage 2 will initiate automatic return home.

提供兩階段電池低電壓保護，第一階段閃燈警示，第二階段啟動自動返航。



Smart

APS-M provides 3 intelligent flight modes: CFO, HCL, and POI.

具有航向鎖定、返航點鎖定、定點環繞三種智能飛行。



OSD

Provides real-time OSD flight data output function.

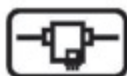
提供OSD飛行及時資訊輸出功能。



G

Support G2/G3 gimbal control

支援G2/G3雲台控制。



S

Supports Spektrum and JR satellite receivers.

支援Spektrum與JR衛星天線。



S.BUS
X.BUS

Supports Futaba S.BUS / JR X.BUS / FS iBUS.

支援Futaba S.BUS / JR X.BUS / FS iBUS功能。



iOS

Configuration changes through iOS APP.

支援iOS手機APP調整功能。



Android

Configuration changes through Android APP.

支援Android手機APP調整功能。



Blue
tooth

Supports Bluetooth connectivity with smartphones.

支援藍牙功能，可透過手機設定調整。



RoHS

RoHS certified.

符合RoHS限用規章。

CAUTION
注意

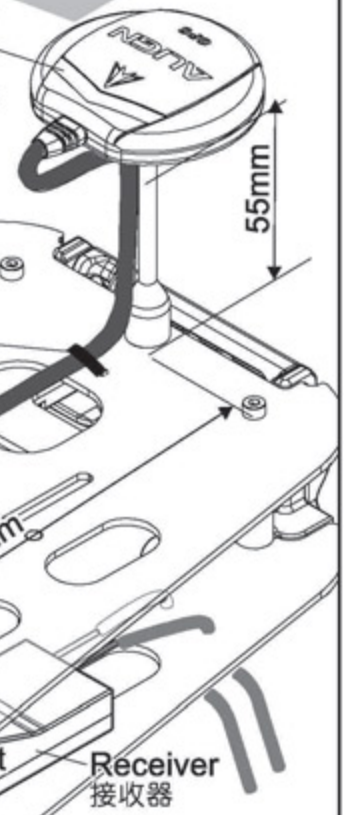
- Install APS-M Multicopter GPS Sensor with arrow pointing toward front of the multicopter on GPS mount to avoid interference with power and video transmission system.
- Follow the instruction manual exactly for ESC signal wire connection. Incorrect connection may result in abnormal multicopter control behavior.
- APS-M utilizes a magnetometer which is prone to interference from surrounding environment. Keep it away from servos, ESC, magnets, iron metals, batteries, power wires, and other electrical components. Any strong magnetic field will cause poor attitude stability and affect the APS-M flight performance.
- Wireless transmission signal may cause interference to the APS-M, affecting the position hold performance. It should be kept away from wireless transmitter and its antennas (such as RF module antenna).
- 安裝APS-M多軸GPS感應器時請依照面板上指示朝機頭方向安裝於GPS固定座上，以避免電池電源及無線通訊的設備互相干擾。
- 連接ESC訊號線時，請遵循說明書組裝步驟安裝，連接錯誤會影響多軸機運作異常而造成無法操控的危險。
- APS-M包含磁力計，磁力計很容易受到環境的干擾，安裝時請遠離伺服機、電子變速器、磁鐵、鐵質金屬、電池、電線等影響磁場零組件，避免磁力計讀取到錯誤地球磁場。
- APS-M也會受到無線通訊的訊號干擾，會造成定位控制性能不佳，安裝時請遠離無線通訊設備。

CAUTION
注意



Directional arrow must point toward the front of multicopter.
指示箭頭朝向機頭

APS-M Multicopter
GPS Sensor
APS-M多軸GPS感應器



Wire Straps
束帶1.6x71mm

Front
機頭方向

Wire Straps
束帶1.6x71mm

APS-M Multicopter Control Unit
APS-M多軸飛控系統

Receiver
接收器

FORBIDDEN
禁止

Do not mount with label facing down.
面板標籤不可朝下

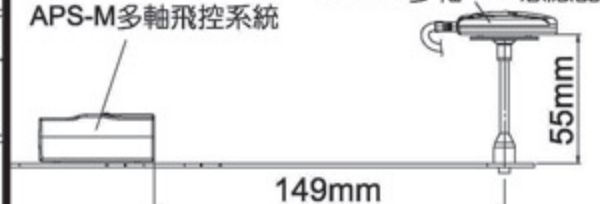


Do not mount with label facing to the side.
面板標籤不可朝向側面



APS-M Multicopter
Control Unit
APS-M多軸飛控系統

APS-M Multicopter
GPS Sensor
APS-M多軸GPS感應器

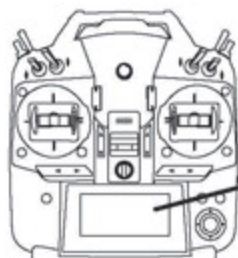


1 SOFTWARE DOWNLOAD AND INSTALLATION

操作介面下載安裝

1. Select either Airplane or Multicopter model type on RC transmitter.
APS-M will only work with transmitter set to either Airplane or Multicopter model type.

遙控器選擇飛機或多軸模式：使用APS-M時，遙控器必須選擇飛機或多軸模式，才能與APS-M正確搭配使用。



2. PC Software Install: Please go to the following website to download the software and install on your PC.

電腦安裝操作介面：下載安裝APS-M電腦操作介面請至下列網址
<http://www.align.com.tw/download-en/apsm/>



If you are having difficulties installing Windows version of the APS-M software, please check whether you have Microsoft .NET Framework 4 installed.
<http://www.microsoft.com/en-US/download/details.aspx?id=17851>

無法安裝APS-M Windows版本時，請檢查電腦是否有安裝Microsoft .NET Framework 4。
<http://www.microsoft.com/zh-TW/download/details.aspx?id=17851>

3. Please scan QR Code for link to ALIGN website to find related software, or search "ALIGN APS-M" in iOS / Android app store. Optional Bluetooth module [HERBT001] is required for connectivity between iOS/Android app and Multicopter.

請掃描QR Code連結亞拓網站下載相關軟體，或是在iOS/Android App store搜尋"ALIGN APS-M"。使用手機下載APP請另購藍牙傳輸器[HERBT001]才能與多軸機搭配使用。

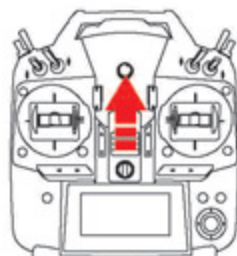


Compatible with

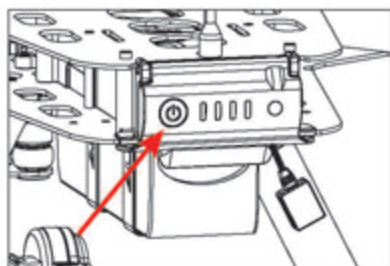


4. Power On Your Transmitter And Multicopter.

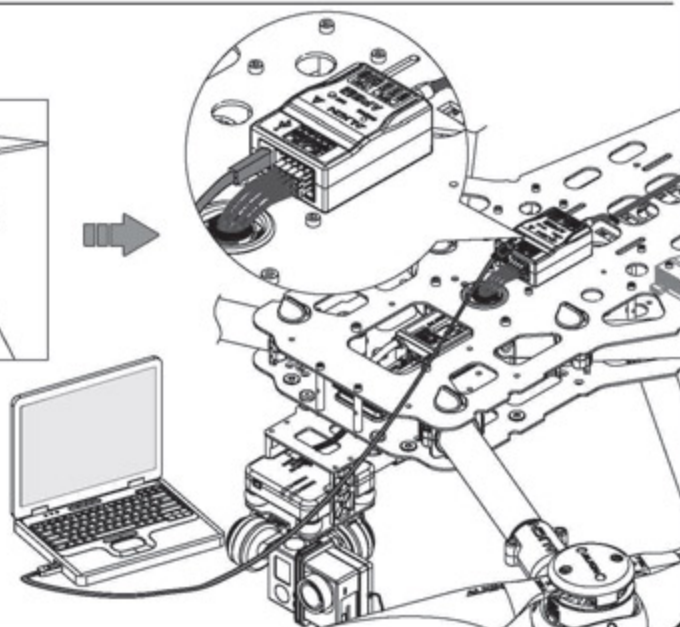
開啟遙控器與啟動電源



Power ON
電源開啟



Press and hold for 3 seconds
to power up
長按3秒開機



2 RC TRANSMITTER SETUP 遙控器設定

1. When using smartphone app to make configuration changes, a Bluetooth password must be set for pairing with the smartphone. The factory default password is "0000". We strongly recommend you to change your password to avoid interference with others during Bluetooth transmission.

Connection Status:

Green:Connected;Red:Disconnected.

使用手機軟體介面(app)調整時，須設定藍牙連線密碼，提供手機連線時使用。預設密碼為"0000"，強力建議使用者先更改密碼後再使用，以免對其他藍牙裝置造成干擾。

連線狀態燈號說明：
綠燈為正常連線；紅燈為未連線。



2. When equipped with PCU Power Control Unit, APS-M will gain power hibernation function where auto power-off will occur in a specific duration after landing.

APS-M's factory default hibernation function is OFF, which can be adjusted to 5 or 10 minutes based on actual needs.

APS-M搭載亞拓PCU電源管理系統，具備智慧電源管理功能，當多軸機降落閒置時，會執行電源關閉保護。

APS-M自動關閉時間原廠預設值為關閉，您可以依實際需求設定關機時間長短，調整至5分鐘或10分鐘關機。



3. RC Transmitter and Receiver:
Please select the receiver type, and confirm the transmitter model type is set to airplane or multicopter.

遙控器與接收器：
請選擇所使用接收器類型。遙控器模式請確認設定為飛機模式或多軸模式。



SATELLITE ANTENNA BINDING

使用衛星天線對頻方式

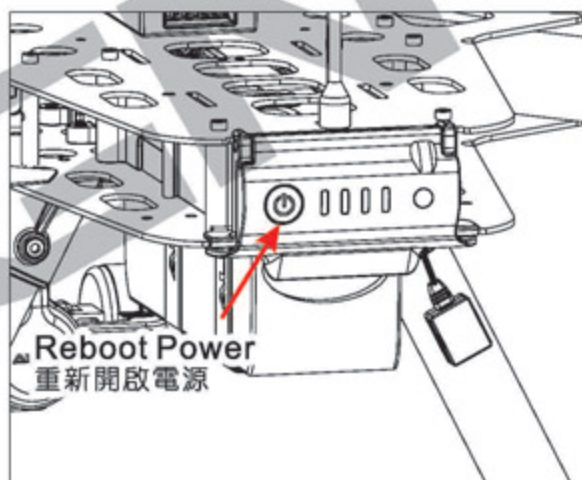
- 1) Binding : (Hold last command)
- 2) Binding with Failsafe: (Go to preset position). Select the " Reverse" on corresponding channels that needs reversing.
 - a) Power on M470, select the satellite receiver type and failsafe type.
 - b) Reboot Power to M470, satellite receiver's LED will blink, indicating entering binding mode.
 - c) Enter the receiver binding mode on your transmitter. Once binding is complete satellite receiver's LED will be steady lit.



1)對頻：(保留最後指令)

2)對頻與失控保護：(回復預設值)

- a) 將M470電源開啟，選擇所使用的衛星天線及失控保護方式。
- b) 重新開啟M470電源，此時衛星天線LED燈會開始閃爍進入對頻狀態。
- c) 將遙控器開啟對頻模式，對頻完成衛星天線LED燈會恆亮。



CAUTION 注意

In binding with failsafe mode, receiver's LED will go from fast blink to off immediately after successful binding, followed by slow blinks. Move the transmitter sticks to desired position to set the failsafe position, which will be confirmed with steady lit of LED after 5 seconds.

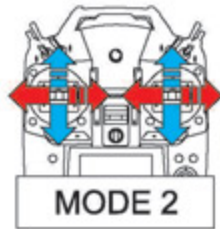
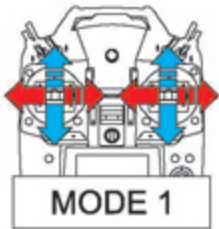
如果選擇"對頻與失控保護"，遙控器對頻完成瞬間，衛星天線上LED會由快速閃爍狀態熄滅，之後再亮起改為慢速閃爍；在慢速閃爍狀態時，將遙控器上的所有搖桿放置於您所需要的預設安全位置，5秒後LED燈會恆亮，完成對頻。

4. RC Transmitter Stick Direction and Travel Range Calibration:

- 1) Before starting, set all EPA / Travel ADJ max and min value on your TX to default 100%, and neutralize all subtrims to 0.
- 2) Move your RC transmitter sticks and confirm travel direction on aileron/ elevator/ rudder/ throttle correctly matches the PC interface display. Select the "Reverse" on corresponding channels that need reversing.

遙控器搖桿方向、行程校正：

- 1) 設定此項目前，所有頻道EPA、Travel ADJ最大最小要為預設值100%，所有微調設為"0"。
- 2) 確認遙控器各動作，副翼、升降、尾舵、油門搖桿方向是否正確，如果介面上顯示方向與搖桿方向相反，可點選該頻道上的"正反向"，讓介面與遙控器一致。



- 3) Select "Calibrate" and move all sticks on RC transmitter to maximum and minimum position, then click on "Complete" to finish.

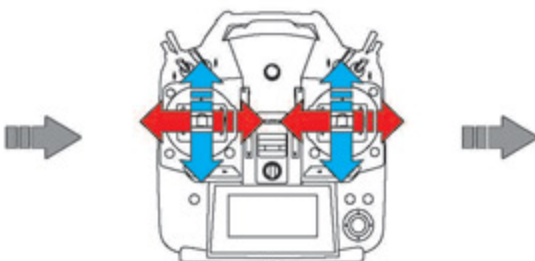
3) 點選"遙控器行程校正"將遙控器搖桿都推至最大、最小，然後按下"完成"來結束校正。



- 1) Click on RC Travel Range Calibraton. 點選遙控器行程校正



- 2) Click on "Calibrate" 點選開始進行遙控器行程校正



- 3) Move all sticks on RC transmitter to maximum and minimum position. 將遙控器搖桿推至最大及最小

- 4) Click on "Complete" 完成

3 CHANNEL FUNCTIONS

各類動作作定義

Attitude, GPS (Velocity), GPS (Angular), Manual, Return Home, Intelligent Flight, as well as Retract functions can all be assigned to individualized switches on your RC transmitter.

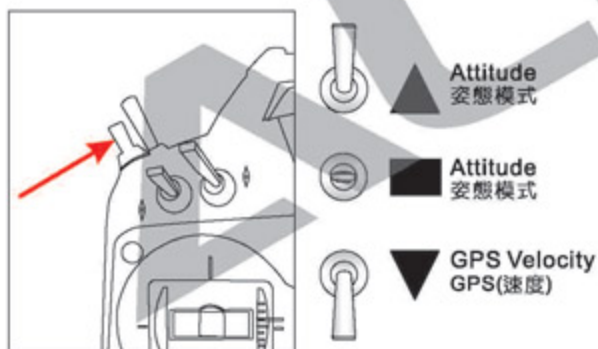
APS-M具備多種飛行模式，姿態、GPS(速度)、GPS(角度)、手動、自動返航、智能飛行與收腳架，可以依喜好習慣選擇指定開關使用。

1. FLIGHT MODES:

- 1) APS-M Flight mode control is on CH5. Assign a 3-step switch on your RC transmitter to CH5.
- 2) Flip the switch and see if correct mode is selected. If slider falls outside the correct position, adjust the EPA/Travel ADJ subtrim in RC transmitter until correct mode is achieved.

飛行模式：

- 1) APS-M飛行模式設置於CH5，請先選擇一個三段開關對應CH5飛行模式。
- 2) 切換開關，查看操作介面上指標是否正確對應到正確位置。如果指標位置錯誤，可用微調與EPA/Travel ADJ功能，將指標調整至正確位置。



CAUTION
注意

Switch settings vary between different transmitter models, and can be set according to user preference.

各型號遙控器開關配置設定不相同，可依使用習慣選擇開關！



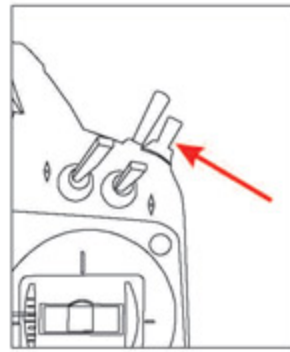
CAUTION
注意

1. Default for first and second position is Attitude mode, but can be changed to Manual using the pull down menu.
2. GPS mode can be switched between velocity and angular GPS mode using the pull down menu.
3. Beginners should not select Manual mode on first position. Inexperiences with manual flying may lead to control difficulties or even crash.

1. 出廠預設值開關第一、二段為姿態模式，可依使用需求，下拉選擇手動模式或姿態模式。
2. GPS模式則有GPS速度模式與GPS角度模式兩種選擇。
3. 初學者不建議設定第一段為手動模式，手動模式在不熟練飛行控制者的操作下飛行，可能會造成不可預期的意外發生。

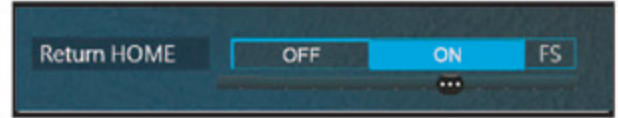
2.RETURN HOME

- 1)APS-M Return Home function is on CH6.
Assign a 2-step switch on your RC transmitter to CH6 for the Return Home feature.
- 2)Flip the switch and see if correct mode is selected. If slider falls outside the correct position, adjust the EPA/Travel ADJ subtrim in RC transmitter until correct mode is achieved



自動返航

- 1)APS-M 返航功能設置於CH6，請先選擇一個兩段開關對應CH6 返航功能。
- 2)切換開關，查看操作介面上指標是否正確對應到正確位置。如果指標位置錯誤，可用微調與EPA/Travel ADJ功能，將指標調整至正確位置。



Failsafe protection and low voltage protection can only be activated with aircraft at least 20M away from home position.

在HOME點半徑20M之內，不執行失控返航、低電壓返航功能。

Failsafe protection

APS-M failsafe protection must work in conjunction with the RC transmitter's failsafe function. Following is a setup example using Futaba T8J:

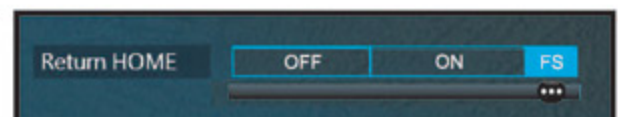
失控保護

APS-M失控保護設定必須搭配遙控器Failsafe功能。以下設定以Futaba T8J為例：

- 1) Activate automatic return home. Adjust transmitter's CH6 Endpoint (EPA) function so the indicator is in the Failsafe region. Write down this Endpoint value for next step.

END POINT	1:AIL	100/100
	2:ELE	100/100
	3:THR	100/100
	4:RUD	100/100
CH6:FLP	5:GER	100/100
L H	6:FLP	100/ 90
100 90	7:AU1	100/100
	8:AU2	100/100

- 1)將自動返航開關開啟，接著調整遙控器Endpoint(EPA)功能中的CH6頻道，將指標調整至"Failsafe"區間。



- 2) Enter the transmitter's Failsafe menu, activate Failsafe on CH6, and enter the Endpoint value obtained in last step.

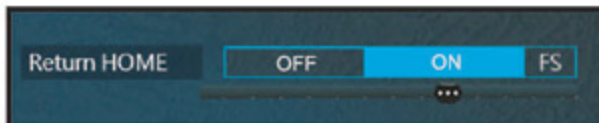
FAIL SAFE (2/2) SFHSS		
5:GER	MOD... POSI	
6:FLP	NOR... - - -	
7:AU1	[FS] + 82%	
8:AU2	NOR - - -	
	NOR - - -	

- 2)進入遙控器"Failsafe"功能，將CH6頻道Failsafe開啓，並將上述調整數值設定至CH6。

3) Then adjust CH6 Endpoint (EPA) function on transmitter so indicator returns to the "ON" region.

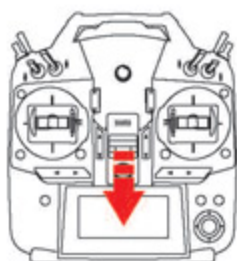
3) 接著將遙控器Endpoint(EPA)功能中的CH6頻道，將指標調回"ON"區間。

END POINT	1:AIL	100/100
	2:ELE	100/100
	3:THR	100/100
	4:RUD	100/100
CH6:FLP	5:GER	100/100
L H	6:FLP	100/ 60
100 60	7:AU1	100/100
	8:AU2	100/100

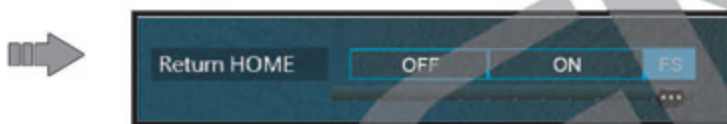


4) Failsafe test: If failsafe is correctly set, the Return Home indicator in the Program Interface will move into the "Failsafe" region once transmitter power is turned off.

4) 失控保護測試，此時可開關遙控電源，設定成功時，介面Return Home指標會移動至"Failsafe"區間。



Power OFF
電源關閉



WARNING
警告

This operation should only be used for testing of failsafe. Do not turn off transmitter while airborne, otherwise loss of aircraft control or other dangerous scenarios may occur.

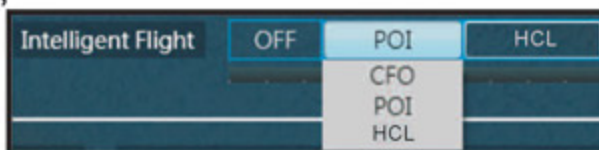
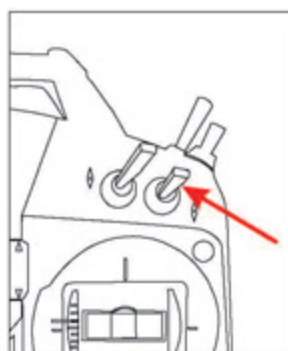
此操作僅供保護設定測試用，嚴禁在飛行中將遙控器關機，以免造飛行機失控與發生不可預期的危險。

4. INTELLIGENT FLIGHT

1) APS-M Intelligent flight mode selection is on CH8. Assign a 3-step switch on your RC transmitter to CH8 for the Intelligent Flight Mode feature.

2) Flip the switch and see if correct mode is selected. If slider falls outside the correct position, adjust the EPA/Travel ADJ subtrim in RC transmitter until correct mode is achieved.

3) APS-M provides 3 intelligent flight modes: POI(Point of Interest), HCL(Home Course Lock), and CFO(Carefree orientation). The flight mode can be selected through pull down menu.



智能飛行

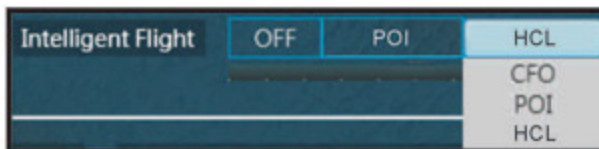
- 1)APS-M智能飛行設置於CH8，請先選擇一個三段開關對應CH8智能飛行。
- 2)切換開關，查看操作介面上指標是否正確對應到正確位置。如果指標位置錯誤，可用微調與EPA/Travel ADJ功能，將指標調整至正確位置。
- 3)APS-M提供三種智能飛行：定點環繞、返航點鎖定及航向鎖定，可依使用需求下拉選擇。

Note:1)The default setting under GPS mode are POI(Point of Interest) and HCL(Home Course Lock).

2)For explanation of Point of Interest, Course Lock, and Home Lock function, please refer to diagrams on page 64~66.

註：1.)出廠預設值為GPS狀態下為定點環繞及返航點鎖定兩種功能。

2.)定點環繞、返航點鎖定及航向鎖定功能，請參考飛行前檢查與注意第64~66頁圖解說明。



Switch settings vary between different transmitter models, and can be set according to user preference.

各型號遙控器開關配置設定不相同，可依使用習慣選擇開關。

4 GIMBAL CONTROL SETTINGS 雲台控制設定

When APS-M is used with G2/G3 gimbals, now you will have full 6 function controls with single RC transmitter: Pan, Roll, Tilt, Shutter Trigger, Panoramic Photo, and Return to Center. User can customize switches on RC transmitter for each of the functions. If you use dual RC transmitter, please pass over to next setting.

APS-M搭配G2/G3雲台使用時，也具備單一遙控器可控制雲台六項功能：Pan軸、Roll軸、Tilt軸、拍照/錄影、環景拍照、一鍵回中，可以依喜好習慣選擇開關使用。使用雙遙控器則跳過此設定。

- 1) First assign the desire function to an RC channel. If the RC transmitter or receiver is 10 channels, you must select 2 functions from the 6 available functions and assign to channel 9 and 10.
- 2) On the RC transmitter select the applicable switch, dial, or slider to map to these 6 functions. We recommend using a dial or slider for gimbal's Pan/Tilt/Roll controls.
- 3) Correct direction for each function. Use the reverse function on RC transmitter to reverse direction if needed.



- 1) 先將所需要使用的功能配置到所要使用的頻道上。如果遙控器或接收機只具備10動作，則從六項功能中選擇會使用到的兩項功能，且將功能配置到第9與第10頻道。
- 2) 在遙控器選擇開關、旋鈕開關或滑軌開關來對應此六項功能。雲台的Pan軸、Tilt軸與Roll軸控制建議設置在旋鈕開關或滑軌開關。
- 3) 確認各功能是否有正常動作，如果動作有反向，可由遙控器的正反向功能切換更改。

The six gimbal control functions can all be assigned to individualized channel on your RC transmitter.

可依喜好將操作介面上的六項雲台控制功能分別配置到所使用的頻道上。



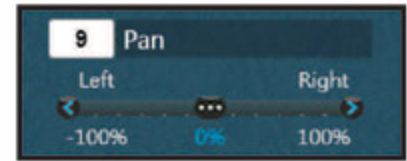
Please set the unused functions to X or N/A.
沒使用到的功能請切換到X或N/A。

GIMBAL CONTROL SETTING INSTRUCTION

雲台控制設定說明：

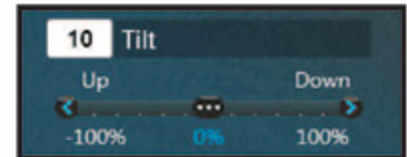
1. Pan control: Control gimbal's pan movement through a designated stick or switch on the RC transmitter.

Pan軸控制：透過遙控器指定一個撥桿或開關，可以控制雲台Pan軸方向動作。



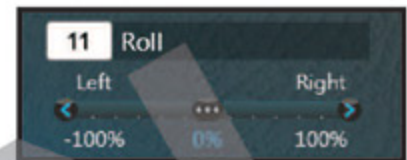
2. Tilt control: Control gimbal's tilt movement through a designated stick or switch on the RC transmitter.

Tilt軸控制：透過遙控器指定一個撥桿或開關，可以控制雲台Tilt軸方向動作。



3. Roll control: Control gimbal's roll movement through a designated stick or switch on the RC transmitter.

Roll軸控制：透過遙控器指定一個撥桿或開關，可以控制雲台Roll軸方向動作。



4. Shutter control: When camera is connected to gimbal's trigger port with optional cable, controls camera's shutter or start/stop recording through a designated stick or switch on the RC transmitter.

拍照/錄影：透過遙控器指定一個撥桿或開關，且雲台與相機需搭配快門線，可以使用遙控器開關來控制相機拍照/錄影功能。

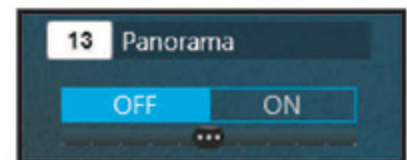


CAUTION
注意

The function doesn't supported by G2 Gimbal.
G2雲台不支援此功能。

5. Panoramic Photo: When camera is connected to gimbal's trigger port with optional cable, allows camera to take panoramic photos at 0-30-60-90 degrees through a designated stick or switch on the RC transmitter. The number of photos taken at each angle is set through control interface program.

環景拍照：透過遙控器指定一個撥桿或開關，且雲台與相機需搭配快門線，可以使用遙控器開關來拍攝水平0度、30度、60度、90度環景照片，各角度拍攝張數可由操控介面調整。

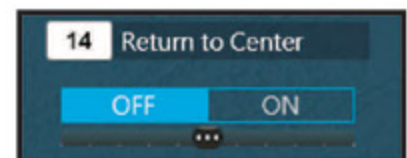


CAUTION
注意

The function doesn't supported by G2 Gimbal.
G2雲台不支援此功能。

6. Return to Center: Return gimbal to center position through a designated stick or switch on the RC transmitter.

一鍵回中：透過遙控器指定一個撥桿或開關，可以使用遙控器開關來讓雲台各動作回到中立點位置。



CAUTION
注意

These gimbal control settings are applicable for single RC transmitter controlling the multicopter and G2/G3 gimbal. RC transmitter and receiver must be 8 or more channels.

此雲台控制設定是運用在單一遙控器控制多軸機與G2/G3雲台時，遙控器與接收機必須具備8動作以上。

5

MULTICOPTER TYPE

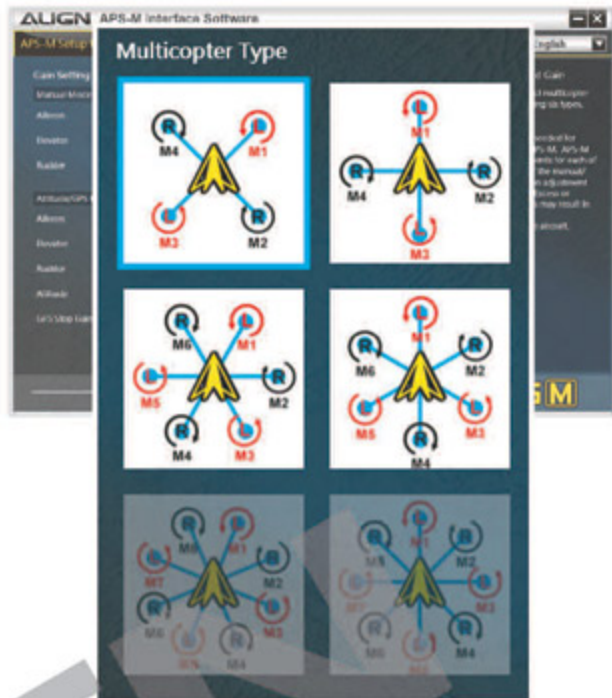
多軸機類型

Please select the correct multicopter layout from the following six types.

Select 4 rotor X configuration for M470

支援六種多軸機類型(四軸、六軸、八軸)，請依所使用的多軸機選擇正確的類型。

M470多軸機請選擇四軸X。



WARNING 警告

Arrow points toward the nose of aircraft. Incorrect type selection may lead to unflyable multicopters or even crash.

指示箭頭朝向機頭，如果多軸器類型選擇錯誤，會造成多軸機無法飛行且有摔毀的危險。

6

GAIN SETTING

感度設定

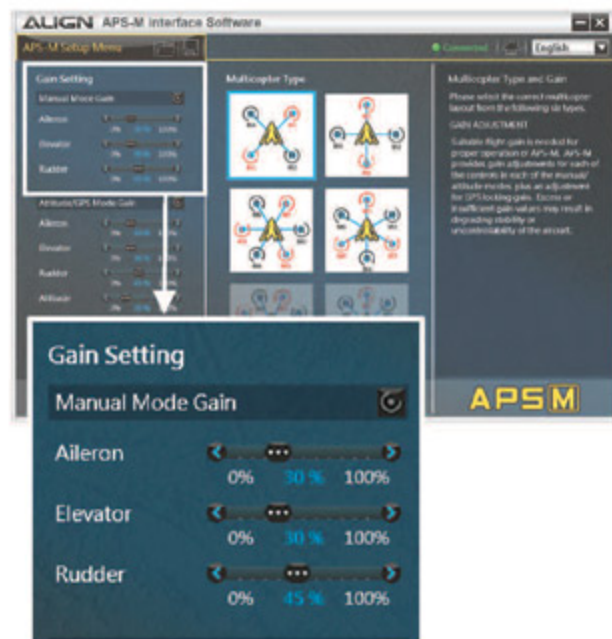
1

GAIN ADJUSTMENT

感度調整

Suitable flight gain is needed for proper operation of APS-M. APS-M provides gain adjustments for each of the controls in each of the manual/attitude modes, plus an adjustment for GPS locking gain. Excess or insufficient gain values may result in degrading stability or uncontrollability of the aircraft.

使用APS-M需設定適當的飛行感度。APS-M提供手動、姿態，模式各動作的感度調整與GPS定位感度。感度過大或過小會造成穩定性或操控性變差。



2 GAIN AND FLIGHT CHARACTERISTICS ADJUSTMENTS

感度與飛行特性調整說明

		Gain too high 感度過大	Gain too low 感度過小
Manual Mode 手動模式	Aileron 副翼	Fast lateral oscillation 機體左右快速抖動	Lateral drift 機體左右不安定滑動
	Elevator 升降	Fast forward/aft oscillation 機體前進/後退快速抖動	Forward/aft drift 機體前進/後退不安定滑動
	Rudder 尾舵	Fast oscillation of the tail 機尾左右快速抖動	Lateral drift of tail 機尾左右不安定滑動
Attitude Mode 姿態模式	Aileron 副翼	Fast lateral oscillation 機體左右快速抖動	Lateral drift 機體左右不安定滑動
	Elevator 升降	Fast forward/aft oscillation 機體前進/後退快速抖動	Forward/aft drift 機體前進/後退不安定滑動
GPS Mode GPS模式	Rudder 尾舵	Fast oscillation of the tail 機尾左右快速抖動	Lateral drift of tail 機尾左右不安定滑動
	Altitude 高度	Fast up/down oscillation during altitude hold, unable to hold altitude 機體高度定位快速抖動	Vertical drift during altitude hold, unable to hold altitude 機體高度上下飄移
GPS Stopping Power GPS煞車		Shorter distance after airframe come to a stop from rapid position holding action 機體停止定位急煞反應，煞車距離較短	Longer distance after airframe come to a stop from delayed position holding action 機體停止定位緩煞反應，煞車距離較長

(Diagram-1) (表-1)

Below are some recommended gain settings and adjustment instructions

以下列出多軸機感度出廠設定與感度調整表

	Manual Mode 手動模式			Attitude Mode 姿態模式				GPS Stopping Power GPS煞車
	Aileron 副翼	Elevator 升降	Rudder 尾舵	Aileron 副翼	Elevator 升降	Rudder 尾舵	Altitude 高度	
M470/M480L multicopter M470/M480L 多軸飛行機	30	30	45	30	30	45	20	0
M690L multicopter M690L 多軸飛行機	30	30	45	30	30	45	20	0

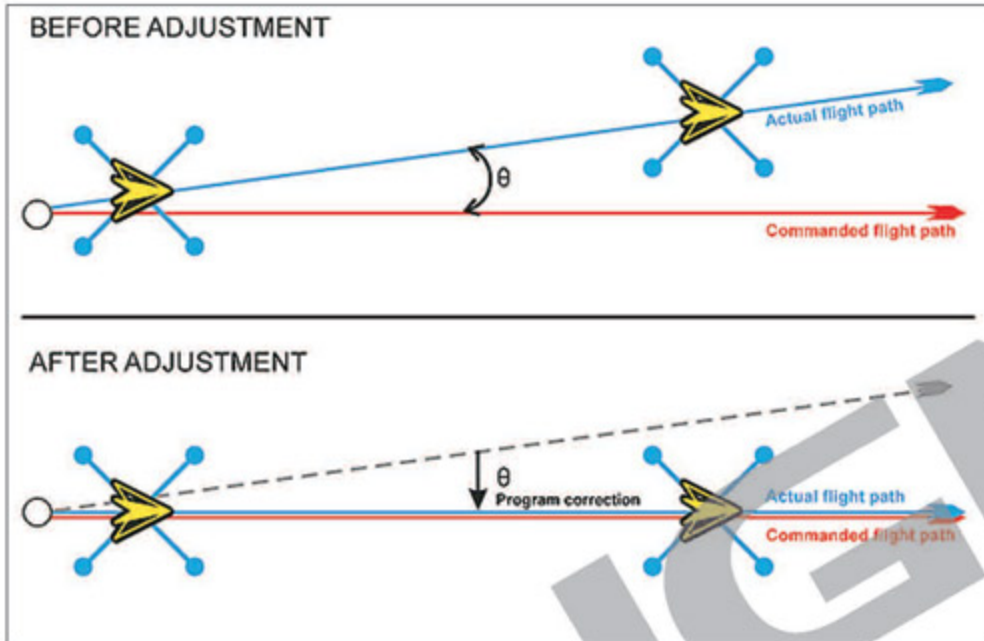
(Diagram-2) (表-2)

7

MAGNETIC FIELD DEVIATION SETTING

磁場偏差值設定

In GPS mode, the multicopter may not fly straight in forward flight because GPS angle will vary from different Magnetic Field Deviation, which means angle on the horizontal plane between magnetic north and true north, and it's positive when magnetic north is east of true north, and negative when it is to the west. To correct the angle value accordingly, APS-M system will automatically adjust the GPS angle value base on where your geographic location is. So please refer to below link of N.O.A.A. Calculator and select your located deviation as following request.



N.O.A.A. Calculator
計算當地磁場偏差數值參考網站
<http://www.ngdc.noaa.gov/g/eomag-web/#declination>

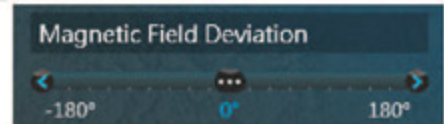
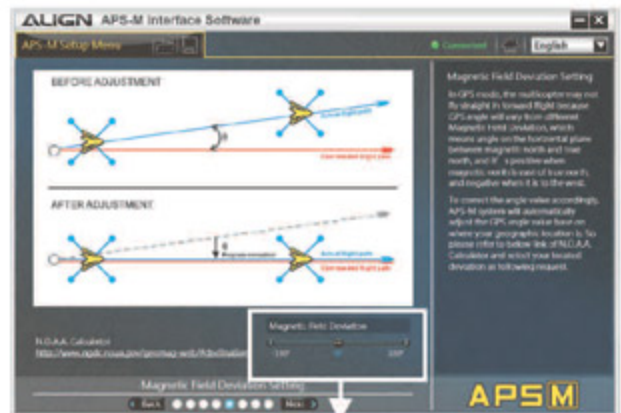
GPS實際飛行路徑會受地磁偏角影響產生偏差值。地磁偏角是地球上任一處的地磁北方向和正北方向之間的夾角，當地磁北向實際偏東時，地磁偏角為正，反之為負。

請根據您目前所在之國家位置，設定相對的GPS偏差角度，系統會自動為您修正偏差值。否則，在GPS的模式下做直線飛行時，可能會產生不同程度的偏移現象。



Magnetic declination requires correct positive or negative polarity.

磁場偏差值有正、負值之分，請輸入正確偏差值。



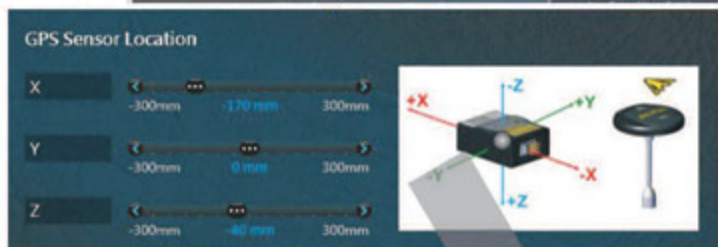
8

APS-M MULTICOPTER GPS SENSOR LOCATION

APS-M多軸GPS感應器位置

1. After APS-M and APS-M Multicopter GPS Sensor are installed onto multicopter, the distance between the two units need to be entered into the system relative to the X, Y, and Z axis, along with the correct direction. The default location values for factory installed APS-M is X: -170, Y:0, Z:-40.

APS-M與APS-M多軸GPS感應器安裝完畢後，需填入GPS感應器與APS-M的相對距離，請依照圖示正確填入X、Y與Z軸距離，並注意方向。出廠時，APS-M已安裝完成，預設值為X:-170、Y:0、Z:-40。



WARNING
警告

Incorrect value or directional polarity of APS-M Multicopter GPS Sensor mounting location will affect aircraft stability or induce drifts.

如果多軸GPS感應器數值方向填寫錯誤，會直接影響飛行器穩定性或飄移。

9

VOLTAGE CALIBRATION

電壓校正

APS-M additional function PCU Voltage Deviation Calibration, the interface shows the latest voltage value detected from PCU. If there is voltage gap between PCU and actual battery voltage value, click on "calibration" and correct actual value accordingly.

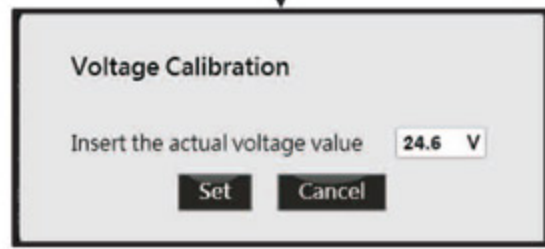
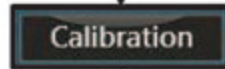
APS-M提供PCU電壓校正功能，操作介面上顯示的數據為目前PCU偵測到的電壓。如果介面上電壓與您使用電池電壓不同時，請點選校正鈕，輸入目前電池實測的電壓數據。



CAUTION
注意

Make sure to turn the multicopter on and firmly connect to APS-M software while testing actual battery voltage by voltage tester (Multi-function Tester RCE-MT9).

測量電池電壓時，請使用電壓檢測器(多功能檢測計 RCE-MT9)，且必須是在多軸機開機並連上操作介面情況下測量。



10 LOW VOLTAGE PROTECTION

低電壓保護

APS-M provides two methods for low voltage protection.

1. First Stage Protection : low voltage warning light

Low voltage warning light: Sets the trigger voltage for low voltage warning. Recommended value is 3.625V, at which point the aircraft will have approximately 200M range left (around 1 minute). When voltage drops below the set value, APS-M LED will be flashing red.

2. Second Stage Protection : low voltage trigger for automatic go home

Low voltage Return Home : Sets the trigger voltage for low voltage return home. We highly recommend the value of 3.60V to be used, at which point the aircraft will have approximately 100M range left (around 30 seconds). When voltage drops below the set value, APS-M will initiate automatic return home feature.



APS-M提供兩種低電壓保護

1. 第一階保護：低電壓警示閃燈

設定低電壓警示閃燈電壓，出廠設定為3.625V(建議值)，此電壓預估可安全飛行距離能力為(約1分鐘)200M，當飛行中電池電壓低於此設定電壓時，APS-M即會閃爍紅燈提醒。

2. 第二階保護：低電壓自動返航

設定低電壓自動返航電壓，出廠設定為3.60V(建議值)，此電壓預估可安全飛行距離能力為(約30秒)100M，當飛行中電池電壓低於此設定電壓時，APS-M即會執行自動返航。



Low voltage protection features require the use of Align PCU.
強烈建議開啓此功能，提供飛行機安全保護。

11 AUTO RETURN HOME HEADING SELECTION

自動返航頭向

Select the multicopter heading toward home position during auto return home.

Front : Nose of multicopter points to home position.

Rear : Tail of multicopter points to home position.

Automatic return home heading default is tail in.

選擇在執行自動返航時，多軸機朝向Home點飛行的頭向

頭：多軸機頭部朝Home點返航。

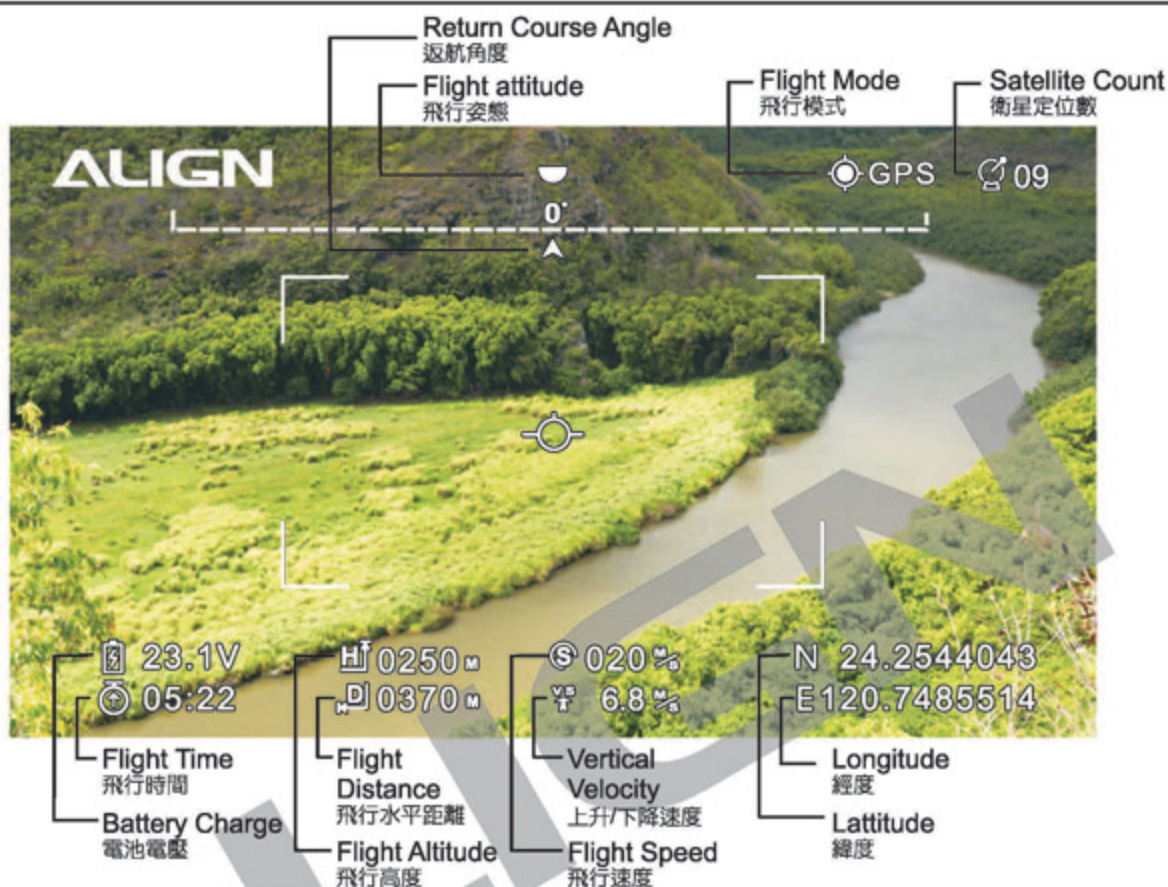
尾：多軸機尾部朝Home點返航。


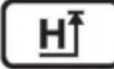
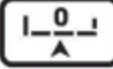
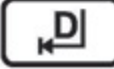








預設為多軸機尾部朝Home點返航。



1 OSD+FPV VIDEO TRANSMITTER DISPLAY DESCRIPTION

OSD+FPV影像發射器畫面圖示介紹



	Flight Attitude : Aircraft's angle of tilt during flight. 飛行姿態：多軸機的飛行傾斜角度。		Flight Altitude : Vertical height between aircraft and home location. 飛行高度：多軸機與Home點的垂直高度。
	Return Course Angle : The angle between aircraft and home position. 返航角度：多軸機頭向與Home點之間的角度。		Flight Distance : Horizontal distance between aircraft and home location. 飛行水平距離：多軸機與Home點的水平距離。
	Flight Mode : The current flight mode of multicopter. 飛行模式：多軸機所使用的飛行模式。		Flight Speed : Horizontal velocity of aircraft. 飛行速度：多軸機水平移動的速度。
	Satellite count : Number of satellites detected by aircraft. 衛星定位數：多軸機接收到的衛星數量。		Vertical Velocity : Speed in which aircraft moves up/down. 上升/下降速度：多軸機垂直移動的速度。
	Battery Charge : Aircraft's battery voltage. 電池電壓：多軸機的電池電壓。		Longitude : Current longitude of aircraft. 經度：多軸機目前所在位置的經度。
	Flight Time : Actual flight duration of aircraft. 飛行時間：多軸機實際飛行時間。		Latitude : Current latitude of aircraft. 緯度：多軸機目前所在位置的緯度。

OPTIONAL EQUIPMENT REQUIRED FOR THIS FUNCTION

此功能須搭配選購商品使用

Optional Equipment
另購品

- 1.OSD+FPV Video Transmitter
OSD+FPV 影像發射器[HED00001]
- 2.Display Receiver
螢幕接收器 [HEM00001]

- 3.GoPro HERO 3/4
GoPro HERO3/4 系列相機

2 OSD+FPV VIDEO TRANSMITTER CONTROL INTERFACE

OSD+FPV影像發射器操作介面

Provides flight data output function such as satellite count, battery voltage, flight time, latitude/longitude, altitude, horizontal distance, horizontal speed, vertical speed, and flight mode.

具備飛行資訊輸出功能，內容有衛星數量、電池電壓、飛行時間、經緯度、高度、水平距離、水平速度、高度速度、飛行模式顯示。

1. OSD display unit and format can be customized based on actual needs.

1. 依實際使用需求選擇OSD顯示單位、格式。



2. OSD display may shift to the side with different display screens. When that happens, use the position adjustment below to center the display.

2. 使用不同顯示螢幕，OSD數據顯示可能會偏移一邊，可以使用下方位置調整功能，將OSD調整至正中位置。



3. OSD also provides warning function which can be set according to your needs. For example, if minimum satellite count is set to 6, the satellite count on LCD screen will flash when APS-M locks on to less than 6 satellites.

3. OSD也具備警示功能，您可以依使用需求設定此功能。例如：設定衛星數為6，當APS-M接收衛星數低於6時，螢幕上的衛星數則會閃爍警示。



When performing motor test function, configuration interface will display the multicopter type, receiver type, low voltage protection parameters, and APS-M Multicopter GPS Sensor position. Please double check the settings match that of multicopter before performing motor test function.

在執行馬達檢測功能時，介面會顯示所設定的多軸機類型與接收器類型、低電壓保護設定參數、APS-M多軸GPS感應器位置；請再檢查是否與目前多軸機的實際狀況相同。

確認無誤後再執行檢測動作。

PCU Power Hibernation

OFF

Multicopter Type

4 rotors x

Receiver Type

Spektrum / JR SAT DSM2



Low Voltage Protection

Battery Specification: 6 cell

1st Stage Protection: 3.625 V

2nd Stage Protection: 3.60 V

Return HOME Heading Direction

Rear

GPS Sensor Location

X: -170 mm

Y: 0 mm

Z: -40 mm

When this function is activated, motor will sequentially rotate approximately 0.5 seconds. Ensure each motor is turning the correct direction, as any incorrect rotating direction may lead to immediate flip-over on takeoff. Rotating motor poses certain danger, so please ensure there are no obstacles or people nearby when performing this test.

使用此功能時，馬達會逐一M1、M2、M3、M4慢速轉動約0.5秒，測試時務必仔細檢視各馬達轉向是否正常，錯誤的轉向將導致起飛時翻機意外，馬達主旋翼轉動過程有危險性，檢測時請先確認多軸機旁無雜物，並且人要避開主旋翼轉動範圍，以免發生危險。



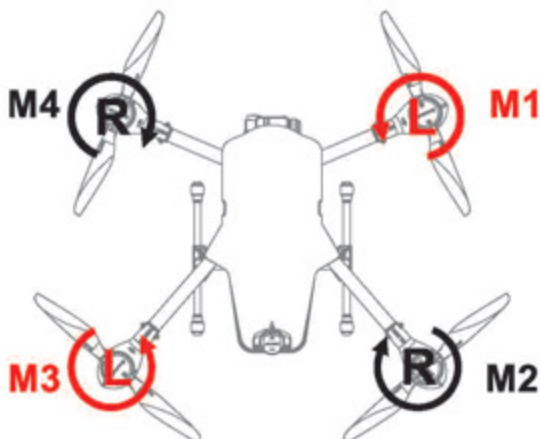
Motor Test

Warning:

1. Each of the motors will rotate slowly for 0.5 seconds during this test. Please ensure there are no obstacles near the rotating blades, and keep all bodily parts away.
2. During the test, motors will rotate sequentially starting with M1. Double check the correct motor is spinning, and the direction of the spin is correct. Do not attempt to fly if any discrepancies is observed.

Begin Test

Begin Test



WARNING 警告

During the test, confirm motor is spinning in sequence from M1、M2、M3、M4, and double check the rotating direction matches the imprint on motor mounting pod. Do not fly if any inconsistency is observed.

檢測時，請確認馬達是否由 M1、M2、M3、M4 依序轉動，請核對是否與馬達座印刷轉動方向正確，如果不正確，請勿飛行。

Revert to Factory Default.

This function will revert all APS-M multicopter flight controller settings back to factory default.

恢復原廠預設值

使用此功能，APS-M多軸飛控系統會將您所設定的內容，恢復為原廠出廠時的預設值。



Reset Factory Default

Reset

GIMBAL POWER ON AND SELF TEST

雲台供電啟動與開機自行檢測

ALIGN

1. POWER UP PROCEDURE WHEN MOUNTED TO ALIGN MULTICOPTERS

Connect the 12V output from Align's PCU with the PCU port on gimbal.

1. 搭配亞拓多軸機開機步驟

由亞拓多軸機PCU輸出DC12V電壓與雲台PCU埠連接。

Turn on RC transmitter power

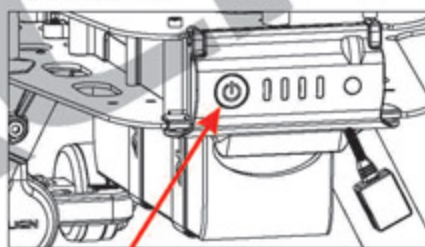
開啟遙控器電源

Turn on gimbal power

開啟多軸機電源



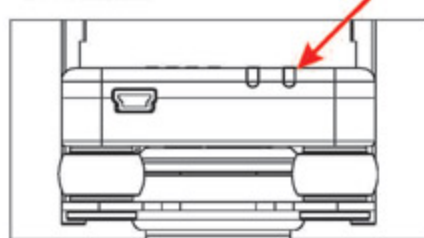
Power ON
電源開啟



Press and hold for 3 seconds to power up
長按3秒開機

Gimbal power up

雲台電源啟動



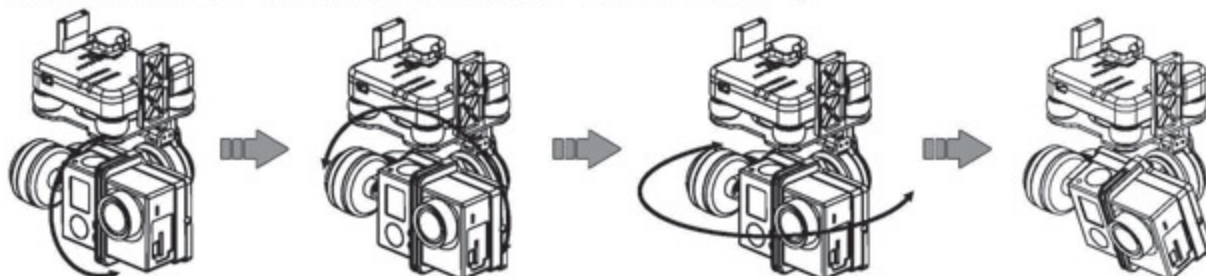
Successful power up is indicated by gimbal 2nd status LED shows green.
雲台狀態指示燈2顯示綠燈，代表開機完成。

2. GIMBAL AUTOMATIC POWER ON TEST.

After power is applied, gimbal will automatically perform 3-axis neutral point calibration. The process takes about 10 seconds, ends with the gimbal locking its heading direction and the camera lens will be down 20 degree. (Factory default setting for Tilt endpoint is 70 degree. If you inquire for larger endpoint setting, please refer to the manual page 54.)

2. 雲台開機自行檢測回中立點

開啟電源後，雲台會自動校正三軸中立定位點檢測，過程約10秒鐘自檢完成，鎖定頭向朝前，鏡頭會向下20度。(TILT可控角度預設為70度，如果有更大角度使用需求，請參考P54設定。)



1 SOFTWARE DOWNLOAD AND INSTALLATION

操作介面下載安裝

1. PC Software Install: Please go to the following website to download the software and install on your PC.

電腦安裝操作介面：下載安裝雲台電腦操作介面請至下列網址
<http://www.align.com.tw/download-en/gimbal/>



If you are having difficulties installing Windows version of the Gimbal software, please check whether you have Microsoft .NET Framework 4 installed.

<http://www.microsoft.com/en-US/download/details.aspx?id=17851>

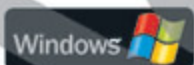
無法安裝Gimbal Windows版本時，請檢查電腦是否有安裝Microsoft .NET Framework 4。
<http://www.microsoft.com/zh-TW/download/details.aspx?id=17851>

2. Please scan QR Code link ALIGN website to find related software, or search "ALIGN Gimbal" in iOS / Android app store. Optional Bluetooth module [HERBT001] is required for connectivity between iOS/Android app and Gimbal.

請掃描QR Code連結亞拓網站下載相關軟體，或是在iOS/Android App store搜尋"ALIGN Gimbal"。使用手機下載APP請另購藍牙傳輸器[HERBT001]才能與雲台搭配使用。



Compatible with



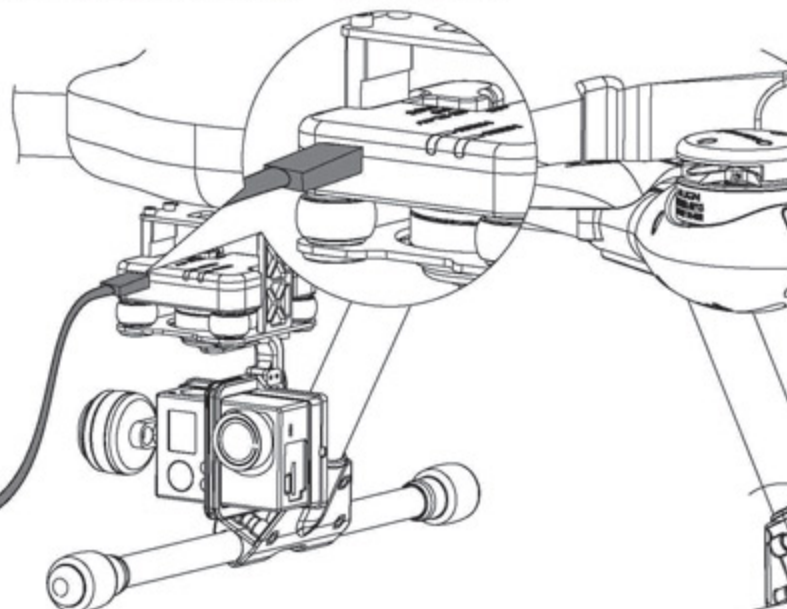
3. Apply power to gimbal. After gimbal's initialization routine is completed, connect to PC with a USB cable to perform setup.

開啟雲台電源，確認雲台自檢開機完成後，使用USB線連結電腦與雲台，進行連線設定。

Connect to gimbal setup interface
與雲台設定介面連線



USB Cable
USB線



2 GIMBAL SETUP

雲台設定

G2 factory default setup is single RC transmitter which can be operated without any further adjustment, but please check and confirm whether radio and APS-M setup is correct (please refer to P37 setup process). If any other flight function need to be added, please enter into advanced setup adjustment.

G2雲台出廠預設為單控模式，需確認遙控器與APS-M設定是否正確(請參考P37頁設定)，G2雲台不須再設定調整即可立即使用。若有其他使用需求，則可進入進階設定調整。

When using smartphone app to make configuration changes, a Bluetooth password must be set for pairing with the smartphone. The factory default password is "0000". We strongly recommend you to change your password to avoid interference with others during Bluetooth transmission.

Connection Status:

Green:Connected ; Red:Disconnected.

使用手機軟體介面(app)調整時，須設定藍牙連線密碼，提供手機連線時使用。預設密碼為"0000"，強力建議使用者先更改密碼後再使用，以免對其他藍牙裝置造成干擾。

連線狀態燈號說明：
綠燈為正常連線；紅燈為未連線。

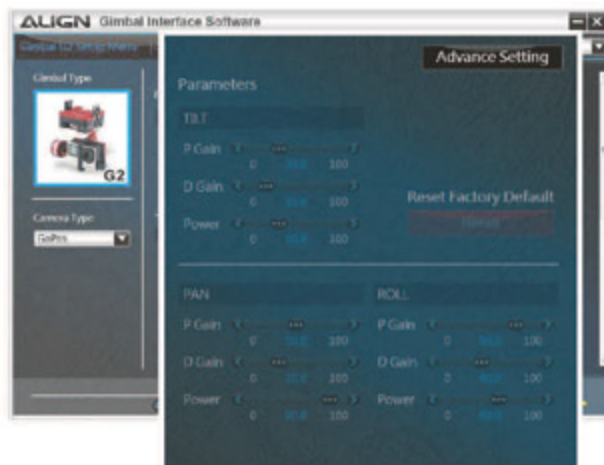


GIMBAL GAIN ADJUSTMENT

雲台感度調整

After selecting the gimbal and camera type, the system will populate all parameter values with optimal values, and gimbal will be ready to function with optimal compensation. "Advanced Parameters" menu is not recommended.

選擇完雲台與使用的相機類型，系統就會輸入最佳內建參數，雲台即能正確運作且具最佳修正效果。不建議調整"進階參數調整"選項。



P.D.POWER PARAMETER ADJUSTMENT

P.D.POWER參數調整說明

	Gain too low 感度過小	Gain too high 感度過大
P Gain	Slow compensation, lagging reaction 修正速度慢，反應跟不上	Over-compensate 修正過頭
D Gain	Cause oscillation of gimbal motors 會造成雲台各軸控制臂修正抖動現象	Motor oscillates or vibrates 馬達抖動、震動
Power 鎖附力量	Insufficient holding power, unable to lock 鎖附力不足，無法鎖定	Motor oscillates or vibrates 馬達抖動、震動

3

GIMBAL CONTROL SETUP

雲台控制設定

1 RECEIVER TYPE

接收器類型

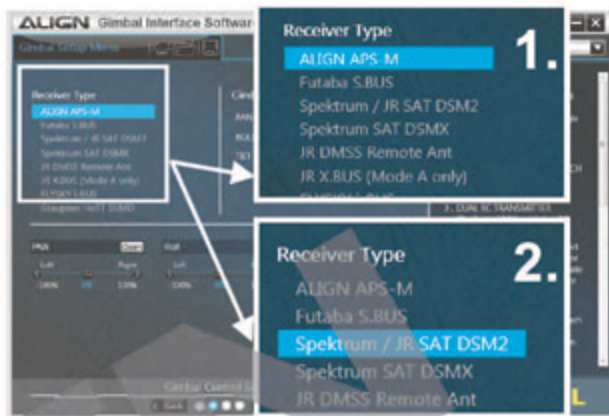
Advanced Setup

SINGLE RC TRANSMITTER AND DUAL RC TRANSMITTERS CONTROLLING MODES

單一遙控器與雙遙控器設定

Gimbal RC operator modes is set here. Align gimbals feature two type of RC operator modes: single RC transmitter and dual RC transmitters controlling modes.

此功能是設定雲台遙控器使用方式，亞拓雲台具備單一遙控器、雙遙控器，兩種遙控器使用方式。



注意

The factory default of G2 Gimbal RC operator mode: Single RC Transmitter

G2雲台預設為單一遙控器模式。

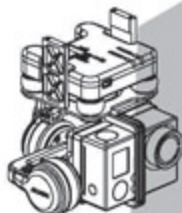
1. APS-M SINGLE RC TRANSMITTER

(Dedicated 10CH or higher RC transmitter for gimbal and multicopter)

This mode requires the use of Align APS-M. Select APS-M in the receiver selection menu.

1. APS-M 單一遙控器 (飛行機與雲台共用同一台10CH以上遙控器)

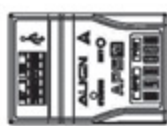
使用此模式需搭配亞拓APS-M使用，在接收器選單裡，請選擇APS-M選項。



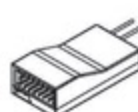
G2 Gimbal
G2雲台組



PCU Power Control Unit
PCU電源控制組



APS-M Multicopter
control Unit
APS-M多輪飛控系統



10CH or more
Futaba S.BUS
/JR X.BUS/ FS iBUS
十動以上接收器



10CH or more
R/C Transmitter
十動以上遙控器

2. DUAL RC TRANSMITTER

(Dedicated 6CH or higher RC transmitter for gimbal)

Gimbal needs to be connected with a S.BUS/X.BUS receiver, or satellite receivers (please refer to page21~23 of manual). Please create a new model in RC transmitter and set the model type to airplane.

2. 雙遙控器 (雲台獨立使用一台六動以上遙控器)

雲台需接上S.BUS/X.BUS接收機或衛星天線 (接線方式請參考說明書第21~23頁)，遙控器請開啟新模型，模型類型選擇飛機類型。

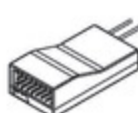


G2 Gimbal
G2雲台組



JR/Spektrum Satellite
衛星天線

OR 或



Futaba S.BUS
/JR X.BUS/ FS iBUS



6CH or more
R/C Transmitter
六動以上遙控器

2 RC TRANSMITTER FUNCTION VERIFICATION 遙控器動作確認

Advanced Setup

Confirm each of the gimbal movement is correctly controlled by the RC transmitter. The control direction can be reversed on the RC transmitter as needed.

確認遙控器操控雲台各動作是否正確，玩家可以利用遙控器正反向功能，來調整雲台動作的正反向。

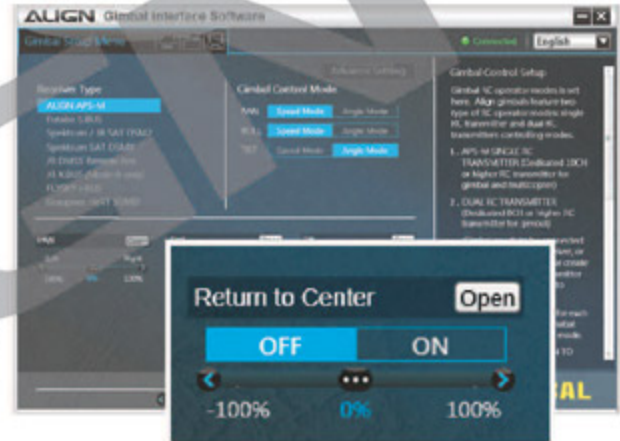
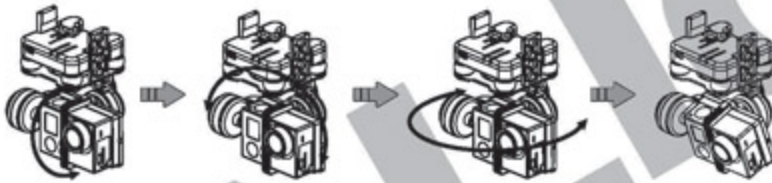


3 RETURN TO CENTER 一鍵回中

Advanced Setup

Returns gimbal to center position through a designated stick or switch on the RC transmitter.

透過遙控器指定一個撥桿或開關，可以使用遙控器開關來讓雲台各動作回到中立點位置。



4 GIMBAL CONTROL MODES 雲台控制模式

Advanced Setup

There are 2 control modes for each of the three axis on the gimbal: angular mode and velocity mode.

雲台3軸的動作具備兩種操控模式，角度模式與速度模式，玩家可以依使用需求選擇操控模式。



1. CONTROLS THE RETURN TO NEUTRAL MODE (ANGLE MODE)

RC transmitter stick movement is translated as angular command. Gimbal will remain centered when the sticks are at neutral position. When stick is moved a certain amount, gimbal will move proportionally the same amount. Larger stick movement equals to larger gimbal movement. When stick returns to neutral, gimbal will return to neutral.

1. 控制角度回中模式(角度模式)

遙控器搖桿控制的角度命令，搖桿在中立點時，雲台會保持在中立點水平位置，當搖桿輸出某動作量時（搖桿動作輸出越大雲台轉動角度越大），雲台動作就會轉動到該動作量的位置，且如果搖桿保持在該動作量，雲台就會保持在該位置，當搖桿回中，雲台就會回到中立點位置。



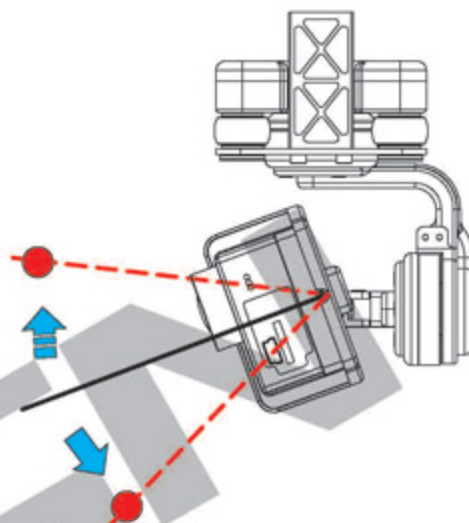
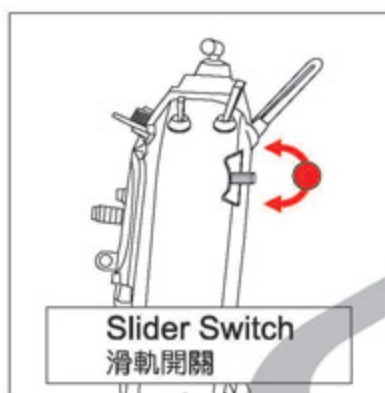
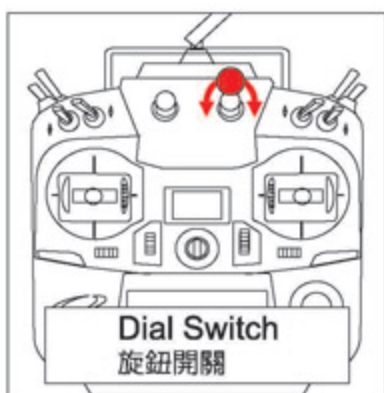
注意

Angular mode is recommended if a dial or slider switch is used on RC transmitter.

使用遙控器旋鈕開關或滑軌開關控制雲台動作，建議使用角度模式。

The larger the stick movement, the more angle gimbal rotates.

搖桿動作輸出越大雲台轉動越大



2. CONTROLS THE ANGULAR LOCK MODE(SPEED MODE)

RC transmitter stick movement is translated as velocity command. When stick is at neutral position, movement command outputs zero, and gimbal remains stationary. When stick is moved a certain amount, gimbal will rotate at a speed determined by stick movement.

Larger stick movement equals to faster gimbal movement. When stick returns to neutral, gimbal will remain at current position (does not return to neutral).

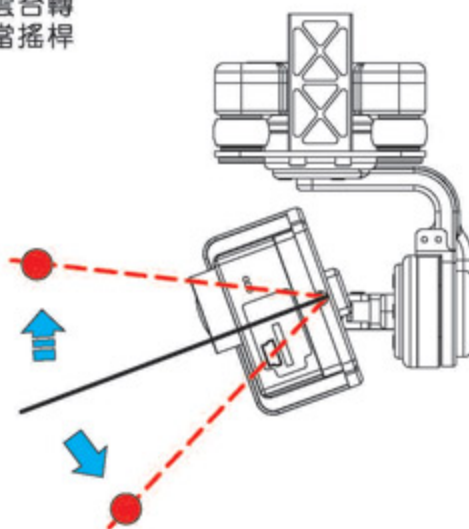
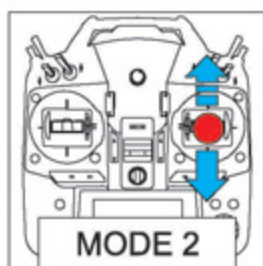
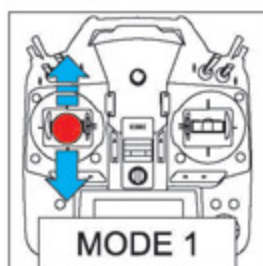
2. 控制角鎖定模式(速度模式)

遙控器搖桿控制為速度命令，搖桿在中立點時，動作為零輸出，雲台不轉動，當搖桿輸出某動作量時（搖桿動作輸出越大雲台轉動速度越快），雲台動作就為以該搖桿輸出量轉動速度，當搖桿回中立點，雲台就會停止在該轉動位置（不回中）。

The larger the stick movement, the faster gimbal rotates.

Stick returns to neutral, gimbal stops at current position.

搖桿動作輸出越大雲台轉動速度越快；
搖桿回中立點，雲台停止在該轉動位置。



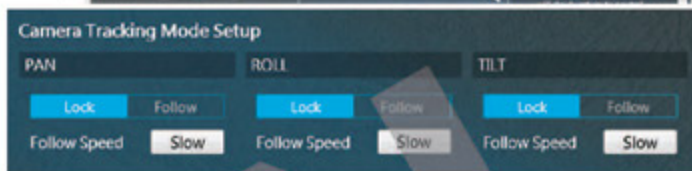
5 MULTI FUNCTION GIMBAL MODES 多功能雲台工作模式

Advanced Setup

CAMERA TRACKING MODE SETUP 相機跟隨功能設定

Each one of the 3 axis of Align gimbal features two working modes: Follow mode and lock mode. The mode can be selected by pilot based on needs. Factory default setting is lock mode.

亞拓雲台3軸各具備跟隨與鎖定兩種工作模式，玩家可依需求選擇雲台的工作模式，出廠預設值為鎖定模式。



1. LOCK MODE

Under lock mode, gimbal will remain fixed to a specific direction regardless of multicopter movement.

1. 鎖定模式

選擇鎖定模式，不管飛行機如何移動，雲台修正時頭向會鎖定在固定方向；遙控器可控制雲台動作。

2. FOLLOW MODE

Under follow mode, gimbal will not lock to a fixed position during compensation; instead it will slowly return to neutral position. For example: If PAN axis is set to follow mode and aircraft initiates a left yaw, gimbal will first compensate, and then slowly return the heading to neutral position.

The velocity in follow mode can be set to fast, medium, and slow.

2. 跟隨模式

選擇跟隨模式，修正時雲台指向會跟隨機體方向回復至原本位置。例如：PAN軸設定跟隨模式，當飛行機往左轉時，雲台PAN軸會先修正，然後頭向再慢慢跟隨左轉回中立點位置。

使用跟隨模式也可以設定跟隨速度，有快、中、慢3種速度，可依使用情況調整。

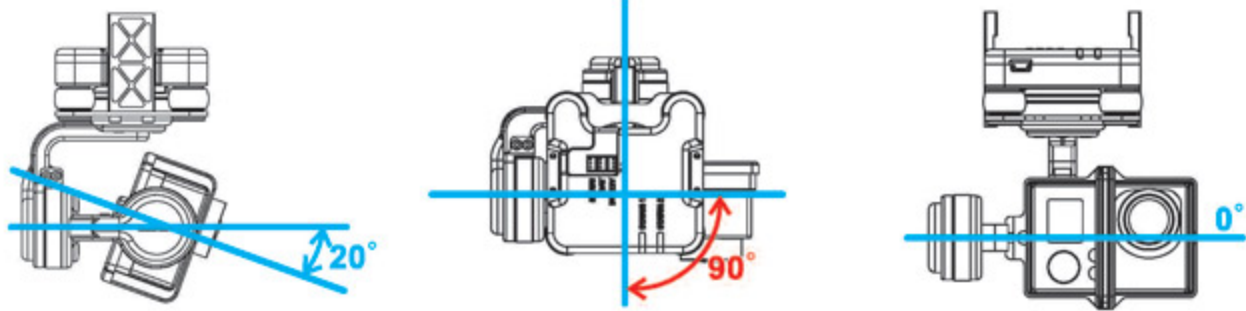
6 GIMBAL CENTER POINT ADJUSTMENT 雲台中立點調整

Advanced Setup

Adjust the center point of each axis on the gimbal. This adjustment can be used to trim the gimbal center point if any of the axis is off-centered.

調整雲台各軸中立點，當雲台中立點有偏移時，可以使用此功能各軸進行中立點微調。





7 PAN AXIS OFFSET COMPENSATION 偏移補償

Advanced Setup

Offset compensation is one of the gimbal's advanced adjustments. If gimbal centers normally, this function does not need to be adjusted. If gimbal exhibits off center movements, this setting can be adjusted to compensate for movement shifts.

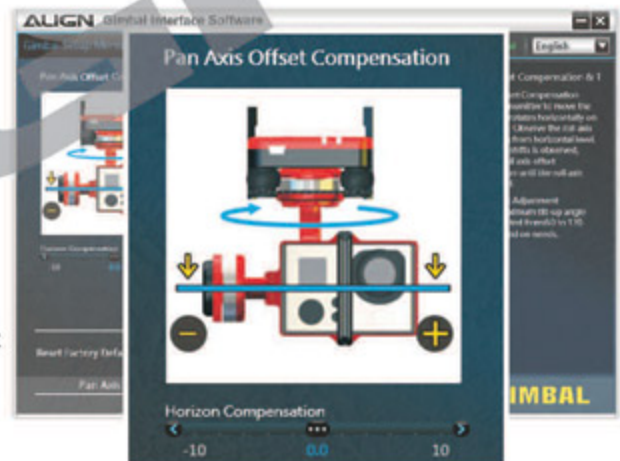
偏移補償為雲台進階調整功能，如果雲台運作正常無偏移情況，則不須調整此功能。當雲台有動作偏移情況，可以透過此功能進行動作偏移補償調整。

PAN AXIS OFFSET COMPENSATION

Using RC transmitter to move the gimbal so it rotates horizontally on the pan axis. Observe the roll axis for any shifts from horizontal level. If horizontal shifts is observed, adjust the roll axis offset compensation until the roll axis remains level.

Pan軸偏移補償

操控雲台Pan軸，使雲台的頭向水平旋轉，觀看Roll軸水平是否有動作偏移。假設Roll軸有偏移，則調整Roll軸數值，使Roll軸動作不偏移。



8 TILT ENDPOINT ADJUSTMENT TILT軸可控角度設定

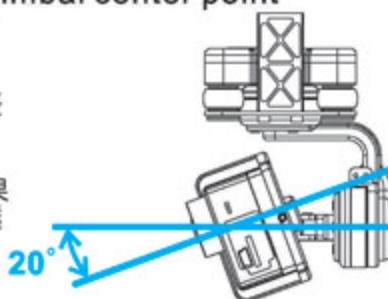
Advanced Setup

Gimbal's maximum tilt-up angle can be adjusted from 60 to 120 degrees based on needs.

Factory default setting for G2 Tilt endpoint is 70 degree. If you inquire for larger endpoint setting, you can adjust the value from Gimbal software. Please do not adjust in gimbal center point adjustment.

提供雲台Tilt軸可控角度設定，玩家可以依使用需求調整Tilt軸可控角度60度~120度。

G2雲台出廠預設為70度，如果您有更大角度使用需求，可透過此功能來調整，請勿使用中立點設定來調整。



PRE-FLIGHT CHECKLIST AND WARNINGS

飛行前檢查與注意

ALIGN

1 LOCATE AN APPROPRIATE LOCATION

遠離障礙物與人群

R/C aircraft can fly at high speed, thus posing a certain degree of potential danger. Choose a legal flying field consisting of flat, smooth ground without obstacles. Do not fly near buildings, high voltage cables, or trees to ensure the safety of yourself, others, and your model. Avoid location with magnetic and radio interferences. Please choose a legal flying field. Do not fly your model in inclement weather, such as rain, wind, snow or darkness.

遙控飛行機飛行時具有一定的速度，相對的也潛在著危險性，場地的選擇也相對的重要，請需遵守當地法規到合法遙控飛行場地飛行。必須注意周遭有沒有人、高樓、建築物、高壓電線、樹木等等，避免磁場干擾、外力訊號干擾及操控的不當造成自己與他人財產的損壞。請務必選擇在空曠合法專屬飛行場地。請勿在下雨、打雷、沙塵等惡劣天候下操作，以確保本身及機體的安全。



2 DO NOT FLY ALONE

避免獨自操控

Before turning on your model and transmitter, check to make sure no one else is operating on the same frequency. Frequency interference can cause your model, or other models to crash. The guidance provided by an experienced pilot will be invaluable for the assembly, tuning, trimming, and actual first flight or unforeseen danger may happen. (Recommend you to practice with computer-based flight simulator.)

至飛行場飛行前，需確認是否有相同頻率的同好正進行飛行，因為開啓相同頻率的發射機將導致自己與他人立即干擾等意外危險。遙控飛行機操控技巧在學習初期有著一定的難度，要盡量避免獨自操作飛行，需有經驗的人士在旁指導，才可以操控飛行，否則將可能造成不可預期的意外發生。(勤練電腦模擬器及老手在場指導是入門必要的選擇)



3 CENTER OF GRAVITY ADJUSTMENT

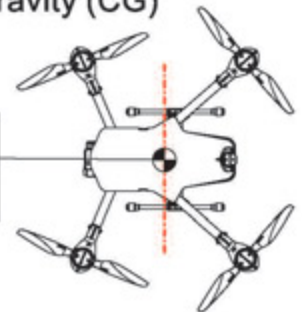
重心調校

The aircraft needs to be balanced at the Center of Gravity (CG) point with full payload onboard. Improper CG balance may cause flight instability and/or uneven power consumption of the motors, and may even leads to crash in worse case scenario.

飛行前務必確認，並調整好全載重機體的重心位置，偏移的重心容易導致飛行不穩與馬達受力不均的耗電、損傷，嚴重將導致不可預期的失衡摔機。

Center of Gravity (CG)
重心位置

M470 Center
of Gravity (CG)
M470重心位置

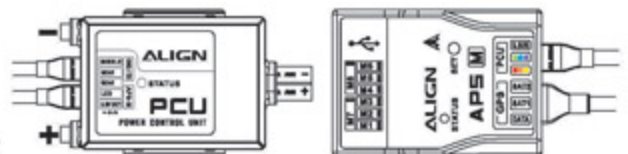


4 CHECK THE WIRE DIRECTION

檢查插線

Make sure to install the wires with "UP" imprint facing up, and ensure the plug is inserted deep enough. Improper plug insertion may lead to poor connection or even malfunction of the APS-M unit.

插線時，請務必將刻有UP字樣端口朝上，對準插座後，確實將插頭完全插入到底，若無確實插入定位，將導致接觸不良、APS-M不動作問題產生！



5

MOTOR START AND STOP

馬達電源啟動與關閉

Safety feature to allow spin-up of motors only when specific transmitter stick movement is executed, so that accidental start/stop is prevented.

1. To Start Motor

- 1) Turn on transmitter power.
- 2) Press and hold power button for 3 seconds to turn on multicopter power.
- 3) Start the motor by pushing both RC transmitter control sticks toward lower inner or lower outer position.

Safety Mode 1: Motors will power off if throttle is not raised within 5 seconds. To re-start Motor by pushing both RC transmitter control sticks toward lower inner or lower outer position.

Safety Mode 2: Motors will power off automatically after landing and throttle is lowered, even without the shutoff routine.

馬達具備安全保護裝置，必須執行遙控器動作才能啟動或關閉馬達電源，避免因誤開電源而啟動或關閉馬達。

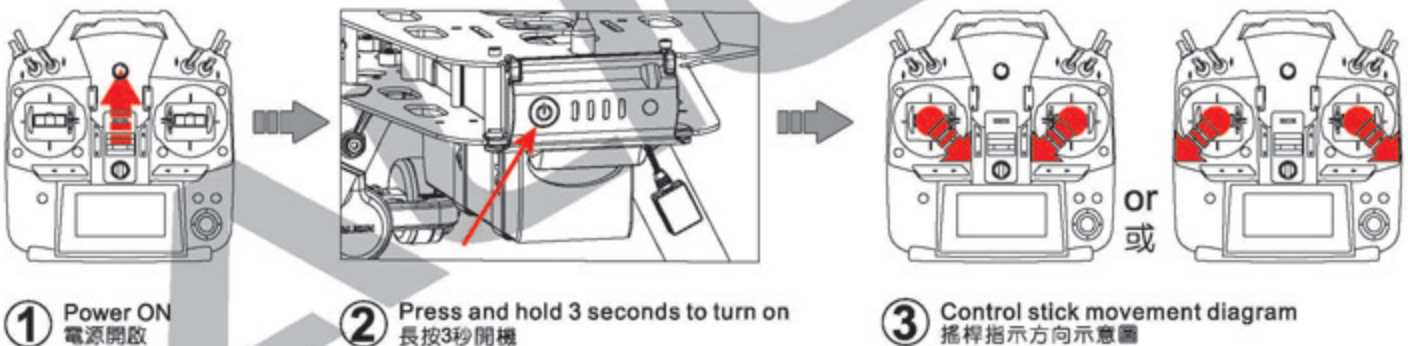
1. 開啓馬達電源

- 1) 開啓遙控器電源。
- 2) 啓動機身主電源，長按電源鍵3秒開機。
- 3) 將遙控器兩支搖桿同時向內向下45°或向外向下打45°，才會啓動主馬達。

安全模式1：當啓動馬達後若5秒內未推升油門，系統會自動關閉馬達電源停止運轉。

如欲再開啓馬達電源，將遙控器兩支搖桿同時向內向下45°或向外向下打45°，才會啓動主馬達。

安全模式2：當飛行完後降落地面，油門降至最低點時，如果未手動關閉馬達主電源，5秒後系統會自動關閉馬達主電源停止運轉。

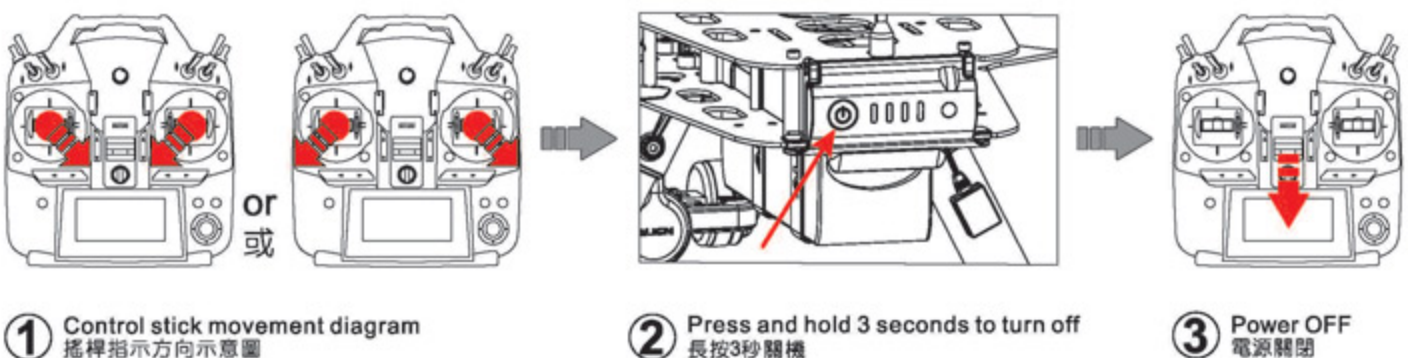


2. To Stop Motor

- 1) Push both RC transmitter control sticks toward lower inner or lower outer position.
- 2) Press and hold the power button for 3 seconds to turn off multicopter power.
- 3) Turn off transmitter power.

2. 關閉馬達電源

- 1) 將遙控器兩支搖桿同時向內向下45°或向外向下打45°，才會關閉主馬達。
- 2) 關閉機身主電源，長按電源鍵3秒關機。
- 3) 關閉遙控器電源。



6

MOTOR SPIN TEST

馬達運轉測試

1. When motor spin test is activated, motor will sequentially rotate approximately 0.5 seconds. Check correct motor location and spin direction is correct.
 2. Rotating motor poses certain danger, so please ensure there are no obstacles or people nearby when performing this test. Please refer to page 45 on motor spin test function in the APS-M installation and Setup manual.
1. 馬達運轉測試功能開啓時，馬達會依序慢速轉動約0.5秒，檢查安裝位置及主旋翼/螺旋槳旋轉方向是否一致。
 2. 馬達主旋翼/螺旋槳旋轉過程有危險性，檢測時請先確認多軸機旁無雜物，並避開主旋翼/螺旋槳轉動範圍，以免發生危險。請參考APS-M操作介面安裝與設定第45頁進行設定顯示與馬達檢測。

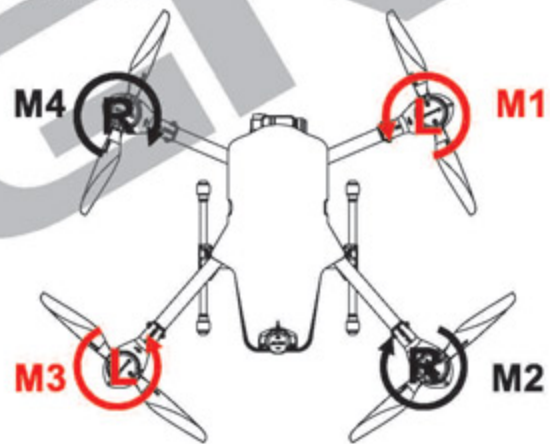
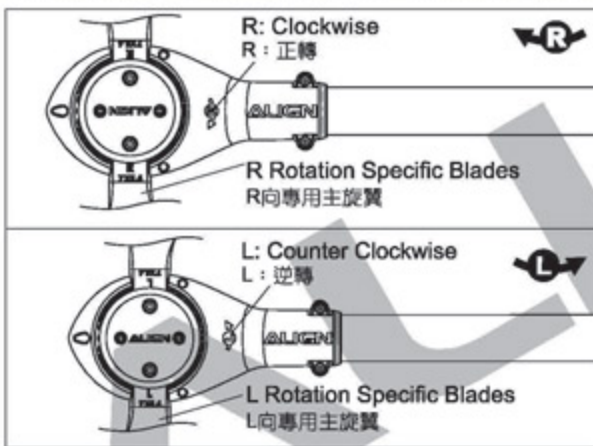
1

MOTOR ROTATION DIRECTION

馬達正逆轉方向

Incorrect sequence of motor tube assembly or changes made to rotational directions of motor / blades may cause immediately flip-over on takeoff.

組裝前請確定馬達固定座上所標示的正、逆轉方向符號；以及前後軸管組長度。



7

MAGNETOMETER CALIBRATION

磁力計校正

Objects on multicopter can interfere with magnetometer's readings, lowering APS-M's heading precision, and even affect position hold ability. To reduce the environmental effect on magnetometer, APS-M must be calibrated prior to use to ensure correct and stable operations. Calibration must be performed whenever one of the following condition occurs:

- The initial install of APS-M modules.
- Changes to the GPS module.
- Additions or removal to electronic equipment near the magnetometer (Servos, ESC, etc).
- When flying location differs from last compass calibration position by **100 km or more**.

磁力計在APS-M裡面是扮演辨別頭向與多軸機姿態的角色，而多軸機上的電子變速器、馬達、電線、鐵性物質等會干擾磁力計，影響APS-M頭向控制的準確度，甚至影響定位控制的效果。為了減少環境對磁力計的影響，所以使用APS-M前務必要執行磁力計校正的工作，才能讓APS-M有正確與穩定運作。

在以下情況，必須做磁力計的校正：

- 第一次安裝APS-M時。
- 更換或移動GPS感應器時。
- 增加或減少磁力計附近的電子裝置（伺服器、電子變速器等）時。
- 當變更飛行場地，位於上一次做磁力計校正動作的位置，兩地相隔距離**100公里**以上時，請必須重新校正一次。



Please perform calibration in open space, at least 10 meters away from strong magnetic field and conductive materials (magnets, metal table, metal buildings, concrete floors, high voltage electrical tower etc). External environment factors may affect the accuracy of magnetometer. Should multicopter experience poor position holding performance while in APS-M flight mode, please perform magnetometer calibration steps again.

請在空曠且遠離強磁和導磁物質10公尺以上（磁鐵、鐵桌、鐵皮屋、鋼筋水泥地板、高電壓線路等）的地方校正。外在環境的改變會影響磁力計的準確度，當多軸機於APS-M飛行模式下，發生定位效果不佳時，請重新校正磁力計。

- APS-M requires a minimum of 7 satellites.
- Red LED indicates insufficient or no satellite signals. Do not fly under this condition.
- 在正常的情况下，APS-M所需衛星數量為7顆。
- 若亮紅燈表示接收不到衛星訊號，或衛星強度不足，禁止飛行。

1. Two methods to enter calibration mode.

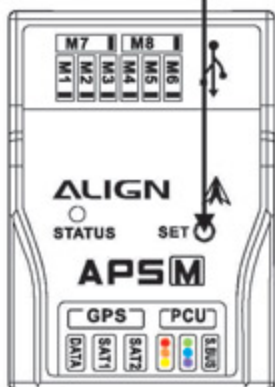
有兩種方式可以進入校正程序

Method 1: Press the SET button on APS-M to enter calibration mode.

方式1：按APS-M多軸飛控系統SET鍵，進入校正程序。

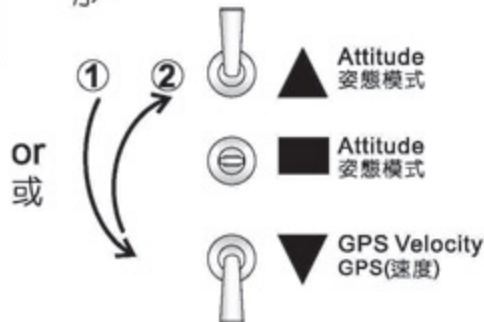
Press once.

按一下



Method 2: Quickly slip the flight mode switch 3 times within 2 seconds to enter calibration mode.

方式2：飛行模式開關在2秒時間內，來回切換3次，進入校正程序。



Switch 3 times

來回切換3次



Steady lit red
紅燈恆亮

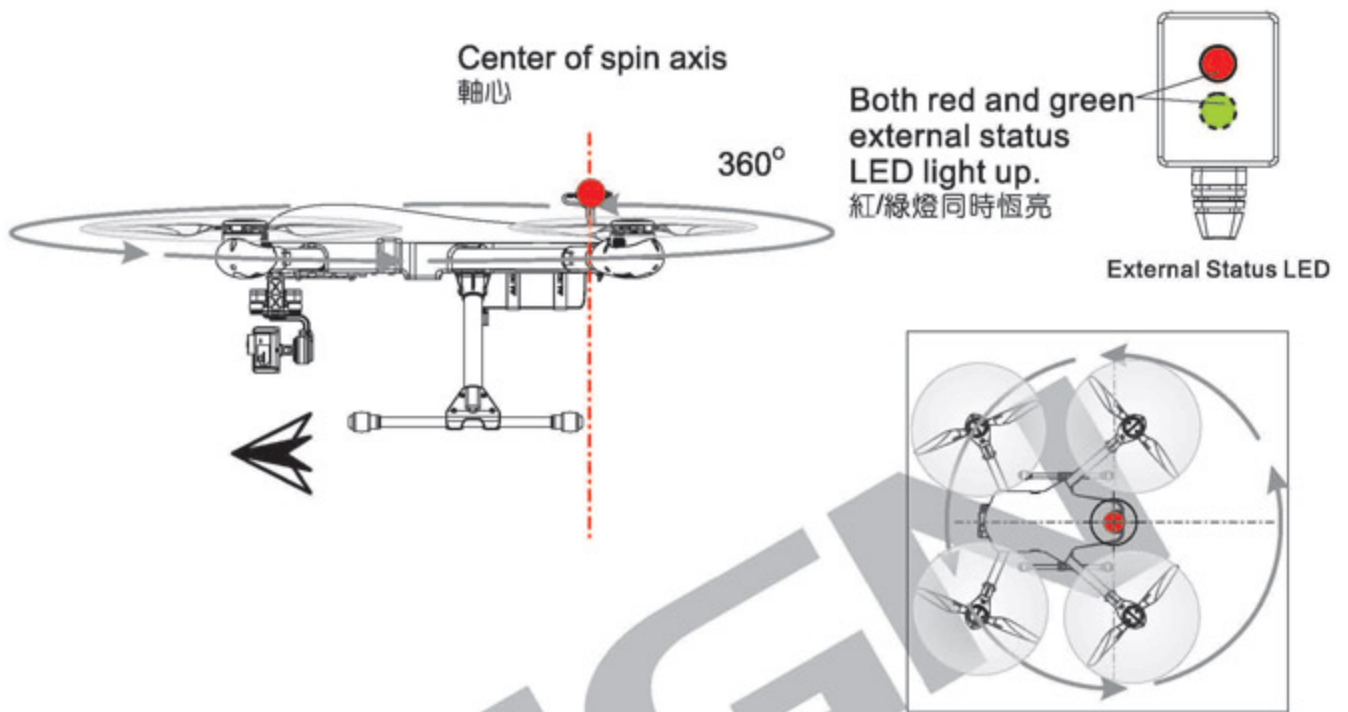
External Status LED

External status LED will light up red when entering calibration mode.

進入校正程序外掛用模式燈會紅燈恆亮。

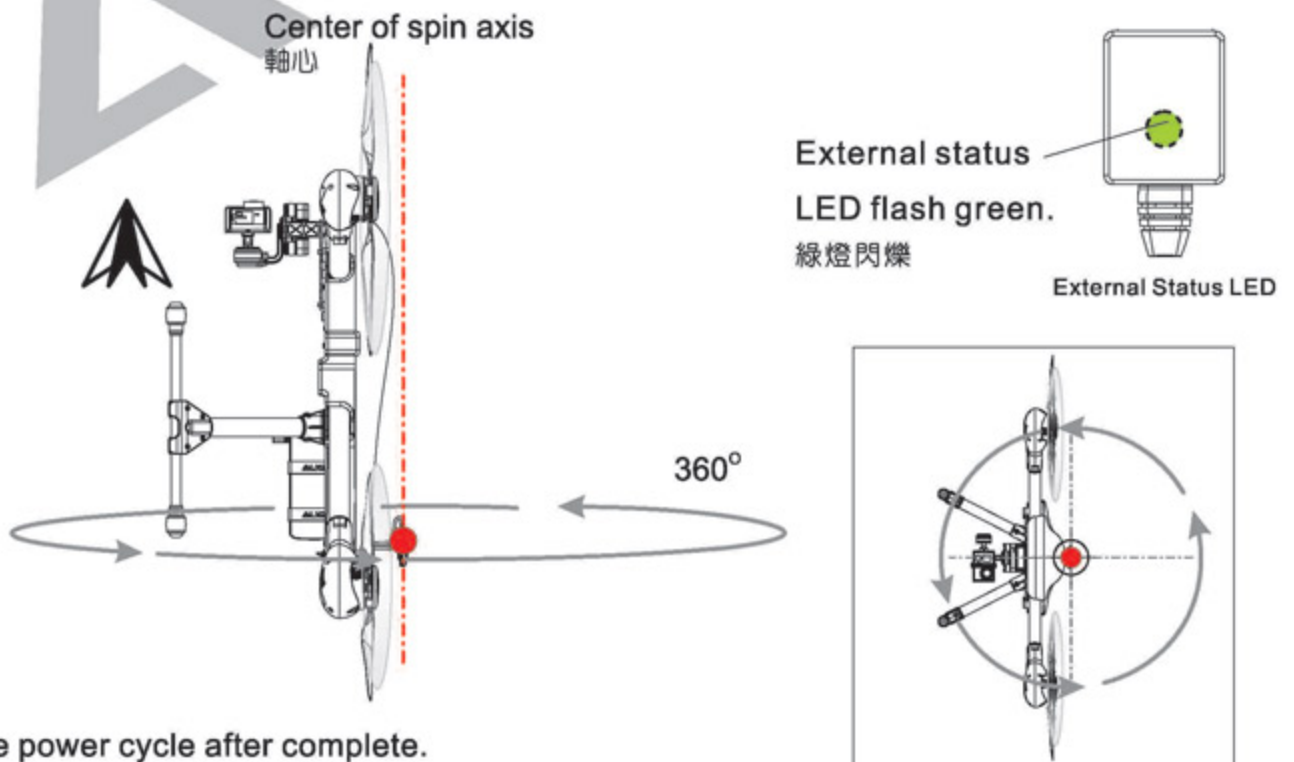
2. Pick up the multicopter. With the APS-M Multicopter GPS Sensor as center of axis, rotate 360° horizontally until both red and green external status LED light up.

拿起多軸飛行機，且以APS-M多軸GPS感應器為軸心，水平旋轉360度直到外掛用模式燈，紅/綠燈同時恆亮。



3. With the nose of multicopter pointing up, and APS-M Multicopter GPS Sensor as center of axis, rotate 360° horizontally until external status LED flash green.

將多軸飛行機朝上立起，以APS-M多軸GPS感應器為軸心，再水平旋轉360度直到外掛用模式燈，綠燈閃爍。



4. Please power cycle after complete.

完成後，請重新開機。

8

HOME POSITION SETTING

返航點設定(HOME)

Setting the home position is a necessary and important step during pre-flight check. The goal of home position setting is for multicopter to properly perform intelligent flight modes and return home feature.

1. After performing magnetometer calibration, the power must be turned off. Once the power is turned back on and satellite lock is acquired, the Home location is recorded for this flight.
2. Power on multicopter. Do not move the multicopter until external status LED turns green.

多軸機Home點設定是必要且是執行飛行前相當重要步驟之一，主要目的讓多軸機在GPS飛行模式下能正確執行各項智能飛行及必要時能安全返航Home點。

1. 第一次飛行執行完磁力計校正後，必須關閉電源，再次開機後，當接收到衛星定位後，此為這次飛行的Home點。
2. 開啓啟動電源，直到外掛用模式燈亮綠燈前，請勿晃動機體。

CAUTION 注意

Avoid setting Home location while indoor, or at location near obstacles within 15 meter such as trees or houses.

禁止於室內、屋簷下、樹下；周遭務必遠離障礙物15公尺以上的地方設定為Home點。

WARNING 警告

Before flying, ensure battery is fully charged, magnetometer calibration has been performed, and confirm HOME position has been registered. If HOME position has not been registered before each flight, and automatic return home or low voltage / failsafe return home was activated during flight, the system will not be able to recognize and accurately fly back to the home position, resulting in deviation from intended path and unexpected fly away, causing damages and unforeseen danger.

起飛前請檢查電源是否足夠，並做好磁力校正，及確實執行HOME點設定。若每次飛行前未確實執行HOME點設定，在飛行時啟動自動駕駛中的自動返航、低電壓自動返航、失控自動返航之功能時，系統將無法辨認並準確的飛回起飛地之HOME點，進而導致飛行航道偏離而飛失，將可能造成財產損失及不可預期的意外發生。

GPS SATELLITE SIGNAL GPS衛星訊號收訊










Flying field 飛行場地	Satellite Signal 衛星訊號	Satellite Count 衛星數量	Time to Satellite Lock 鎖定時間	Status 狀況	Suitable Flight Mode 適用飛行模式
City high rises 高樓市區	Initial Time to Acquire Satellites 第一次接收	7 or more satellites 7以上	60~90sec	Normal 正常	Attitude 姿態
	Succeeding Time to Acquire Satellites 第二次接收	7 or more satellites 7以上	30~60sec		Attitude / GPS 姿態/GPS
		7 or more satellites 7以上	Exceeded 90 sec. 超過90秒	Abnormal, poor or no GPS signal, may lead to incorrect flight position or home position shift. 異常，衛星訊號差或無訊號，會 導致飛行定位及 HOME 點偏移	Attitude 姿態
Open field with no obstructions 空曠無遮蔽物	Initial Time to Acquire Satellites 第一次接收	7 or more satellites 7以上	30~90sec	Normal 正常	Attitude / GPS 姿態/GPS
	Succeeding Time to Acquire Satellites 第二次接收	7 or more satellites 7以上	15~30sec		Attitude / GPS 姿態/GPS
		7 or more satellites 7以上	Exceeded 90 sec. 超過90秒	Abnormal, poor or no GPS signal, may lead to incorrect flight position or home position shift. 異常，衛星訊號差或無訊號，會 導致飛行定位及 HOME 點偏移	Attitude / GPS 姿態/GPS

During initial power up, GPS status indicator will be flashing red. Allow the GPS to remain stationary in open space to acquire GPS signal. The location where initial GPS signal is acquired will become the Home location.

剛開機時，GPS訊號顯示器燈號會紅燈閃爍，在空曠的地方接收GPS訊號需要靜置一段時間，待收到GPS訊號時，首次接受到GPS訊號的位置即為Home點。

FLIGHT MODE STATUS LED DESCRIPTION

飛行模式狀態燈號圖示說明

Description of LED status 其他狀況燈號說明	 GPS Signal First Acquired : Continuously Flash 5 Seconds. 首次接收GPS訊號：綠燈連續快速閃爍5秒		
	 Low voltage alarm : Red Fast Flash 低電壓警示：紅燈快速閃爍	 APS-M Multicopter GPS Sensor Melfunction : Red Flash APS-M多軸GPS感應器故障：紅燈閃爍	 Unsuccessful power on : Solid Red 開機未成功：紅燈恆亮
Flight Mode 飛行模式	No GPS Signal 無GPS訊號	With GPS Signal 有GPS訊號	
Manual Mode 手動模式	 Red Flash 紅燈閃爍	—	
Attitude Mode 姿態模式	 Flash Red/Green 紅/綠燈交叉閃爍	 Flash/Green 綠燈閃爍	
GPS Mode GPS模式	 Red LED flashes 1 sec and Green LED flashes 2 sec alternatively. 紅燈閃爍1秒/綠燈閃爍2秒，兩燈號交叉閃爍	 Slow Flash/Green 綠燈慢速閃爍	

While in GPS mode, green LED indicates normal flight condition. Should LED changes to red color, please land immediately.

在GPS模式下，燈號為綠色表示可正常飛行，若燈號顏色出現紅色時，建議將多軸機立刻停飛降落，避免造成危險與損壞。

Signal acquisition is quicker if in wide open space. If the multicopter is in area with weak GPS reception, only attitude and manual control is available.

若在GPS訊號較弱的地方，沒有足夠穩定的資訊，就只有姿態和手動控制。

1 MANUAL MODE

手動模式

1. Full control by the pilot without any horizontal leveling or position holding capabilities. (Highly recommended not to turn on this function if you're not familiar with it.)
2. Does not support intelligent flight mode (Carefree Orientation or POI), automatic return home, failsafe, or low voltage protection.

1. 完全由操控者控制，無自動水平與定位功能。(強烈建議，不熟悉操作者勿開啟此功能)。
2. 不支援智能飛行(航向鎖定、定點環繞)、自動返航、失控保護、低電壓保護功能。

Control Response adjustment:

Set the exponential (EXP) of Aileron/Elevator/Rudder according to your control feel in manual mode.

When control response is too fast, decrease EXP -10%~60% for Futaba radios ; increase EXP +10%~+60% for JR radios.

When control response is too sluggish, increase EXP +0%~+30% for Futaba radios; decrease EXP -0%~-30% for JR radios.

動作靈敏度調整:

手動模式可依個人飛行操控手感調整遙控器副翼、升降、尾舵的EXP；

當手動模式動作靈敏度太大，Futaba調低範圍-10%~60%；JR的調高範圍+10%~+60%。

當手動模式動作靈敏度太小，Futaba調高範圍+0%~+30%；JR的調低範圍-0%~-30%。



注意

Manual mode is suitable only for experienced pilots. Beginners should avoid flying in manual mode. Following functions will be disabled while in manual mode: automatic return home, intelligent flight mode, failsafe, low voltage return home.

手動模式適合有飛行經驗的玩家使用，並嚴禁初學者使用，否則會造成不可預期的結果。在手動模式下不支援自動返航、智能飛行、失控保護、低電壓保護等功能。

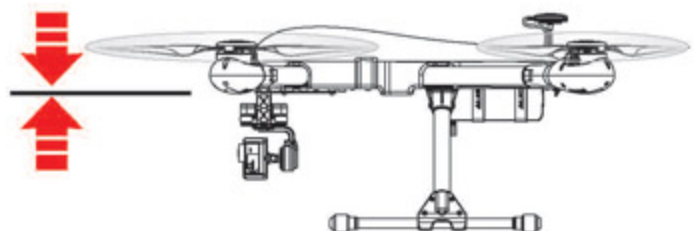
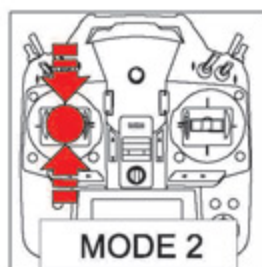
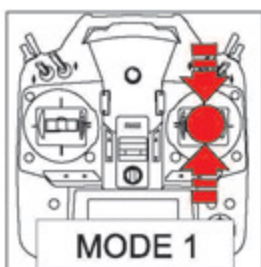
2 ATTITUDE MODE

姿態模式

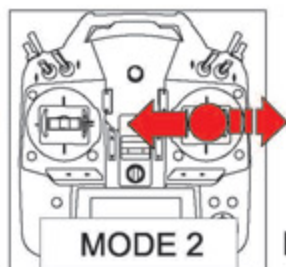
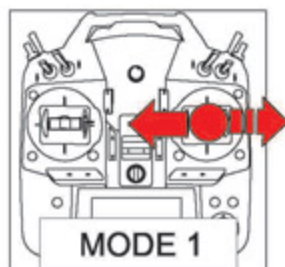
Maintains level and altitude. Elevator/Aileron/Rudder stick inputs are translated as angular command. Larger stick input translates to steeper angles of multicopter tilt, with maximum of 30 degrees.

姿態模式會自動保持多軸飛行機姿態水平與定高功能，升降、副翼、尾舵搖桿指令為角度命令，搖桿動作越大飛行機動作角度越大，最大角度限制為30度。

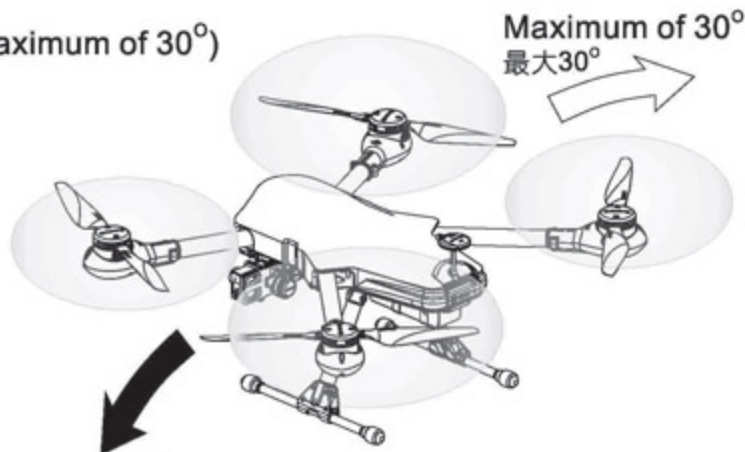
- a) Center stick = altitude hold
油門搖桿置中=定高



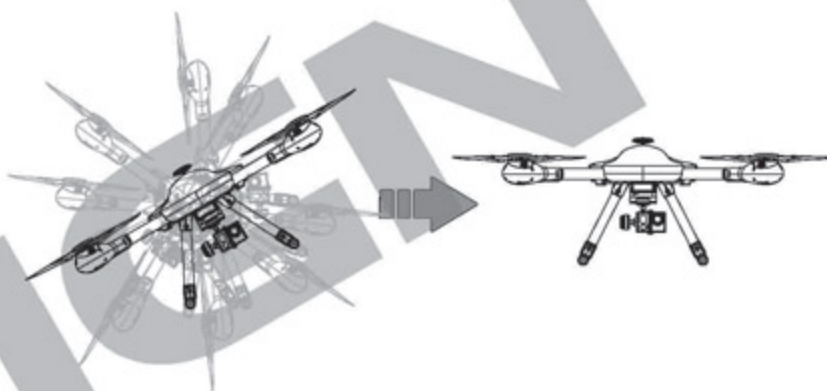
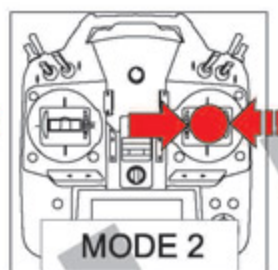
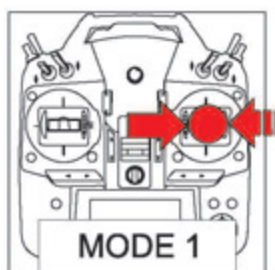
b) Elevator/aileron stick (left and right maximum of 30°)
升降/副翼搖桿(左或右最大30度)



Maximum of 30°
最大30°



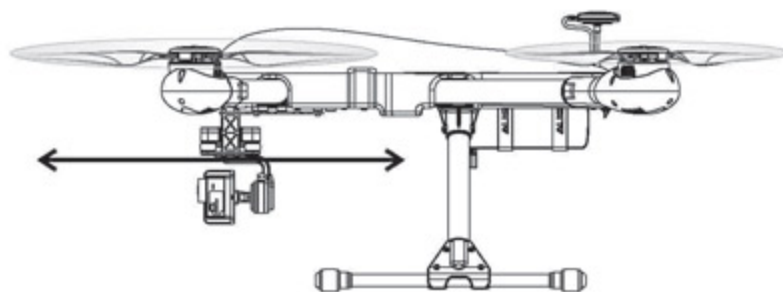
c) Release stick (multicopter automatically levels)
搖桿放開(機體自動回正)



3 GPS(VELOCITY) GPS(速度)

Maintains level, altitude, and position through GPS lock. Elevator/Aileron/Rudder stick inputs are treated as speed command. Larger stick input translates to faster flying speed, with maximum horizontal velocity of 15 meters/sec and vertical speed of 6 meters/sec.

會自動保持多軸飛行機姿態水平、定高與GPS定位，升降、副翼、尾舵搖桿指令為速度命令，搖桿動作越大飛行機飛行速度越快，最大飛行速度水平 15 公尺/秒，垂直 6 公尺/秒。

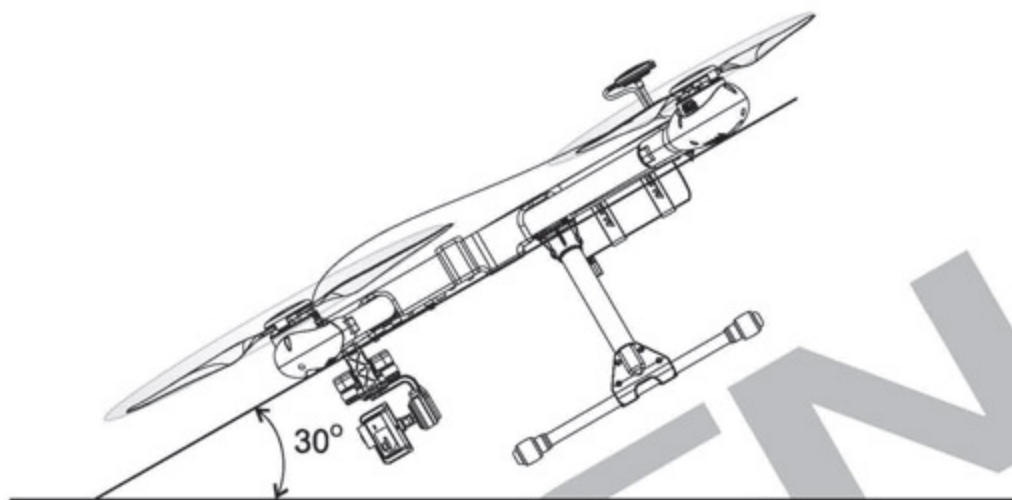


Straight flight speed: 15 m/sec
直線飛行速度：15公尺/秒

4 GPS(ANGULAR) GPS(角度)

Maintains level and altitude. Elevator/Aileron/Rudder stick inputs are translated as angular command. Larger stick input translates to steeper angles of multicopter tilt, with maximum of 30 degrees.

會自動保持多軸飛行機姿態水平與定高功能，升降、副翼、尾舵搖桿指令為角度命令，搖桿動作越大飛行機動作角度越大，最大角度限制為30度。



5 FLIGHT MODE FEATURE CHART 飛行模式功能對照表

Control Modes Function 功能	操作模式 MANUAL MODE 手動模式	姿態模式 ATTITUDE MODE 姿態模式	GPS(VELOCITY) GPS速度	GPS(ANGULAR) GPS角度
Retract 收腳架	✓	✓	✓	✓
Intelligent Flight-POI (Point of Interest) 智能飛行-定點環繞			✓	✓
Intelligent Flight-HCL (Home Course Lock) 智能飛行-返航點鎖定			✓	
Intelligent Flight-CFO (Carefree Orientation) 智能飛行-航向鎖定		✓	✓	
Return Home 自動返航		✓	✓	✓
Failsafe Protection 失控保護	✓	✓	✓	✓
Low Voltage Protection 低電壓保護	✓	✓	✓	✓

1 POI (POINT OF INTEREST)

定點環繞

GPS

POI can only be activated under GPS mode. POI is not supported under manual and attitude modes.

定點環繞只適用GPS模式，姿態和手動模式不支援定點環繞指令。

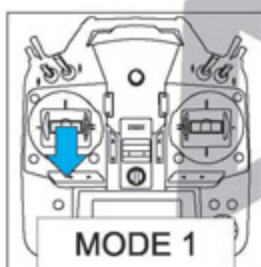
POI (Point of Interest) is a mode where multicopter flies in a circular pattern surrounding a designated object. To initiate POI flight, fly the multicopter over the object of interest in either GPS mode, switch on POI function to set the object location as center point.

1. From the top of POI center point, use back elevator to fly the multicopter backwards at least 10M away from the center point to set the diameter of circular pattern.
2. With the nose of multicopter still pointing at the POI center point, left aileron will initiate a clockwise 360° circular pattern flight around the POI center point; right aileron will initiate a counter-clockwise 360° circular pattern flight around the POI center point.
3. Stick movement angle is proportional to the speed of the aircraft. Larger the stick movement equates to faster multicopter flying speed, while smaller stick movement equates to slower flying speed.

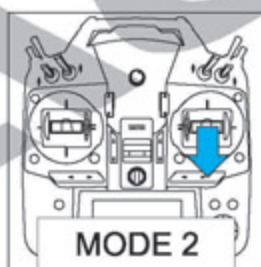
定點環繞是指多軸機朝向指定的一個景物做環繞或攝影的飛行模式。

當需要針對一個景物做360度定點環繞飛行時，請將多軸機飛行至指定物品上空，在GPS模式下，開啓定點環繞功能，即為設定環繞點。

1. 於環繞點上方，將升降舵向後打時多軸機往後飛行，然後退至距離環繞點的位置(至少10M以上)作為環繞半徑距離。
2. 機頭朝著環繞點方向，當副翼持續向左打時，多軸機則會以環繞點做為中心，順時針360度飛行；當副翼持續向右打時，多軸機則會以環繞點做為中心，逆時針360度飛行。
3. 撥桿角度與飛行速度成正比，撥桿角度動作越大則多軸機飛行速度越快；撥桿角度動作越小則多軸機飛行速度越慢。

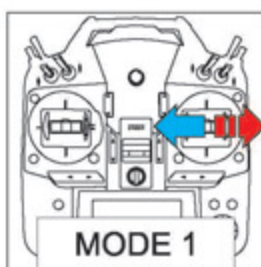


MODE 1

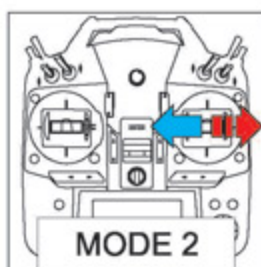


MODE 2

- ① Back Elevator
升降舵向後

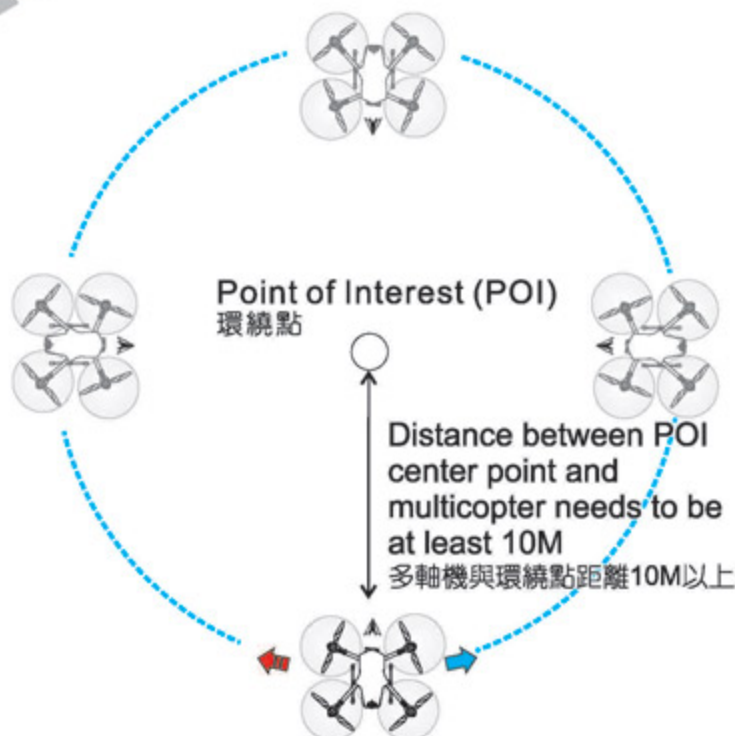


MODE 1



MODE 2

- ② Right or Left Aileron
副翼舵向左或向右



Aircraft can only move backwards, up, and down within 10M after position holding action. Full rudder lock cannot be turned around and it is controlled by APS-M.

定位動作後在10M以內飛行機只能後退、上升、下降，全程尾舵鎖定不能轉頭向，由程式控制。

2 HCL(HOME COURSE LOCK) 返航點鎖定

GPS

Home Course Lock is only active in GPS Velocity mode. Manual and attitude modes do not support home course lock.

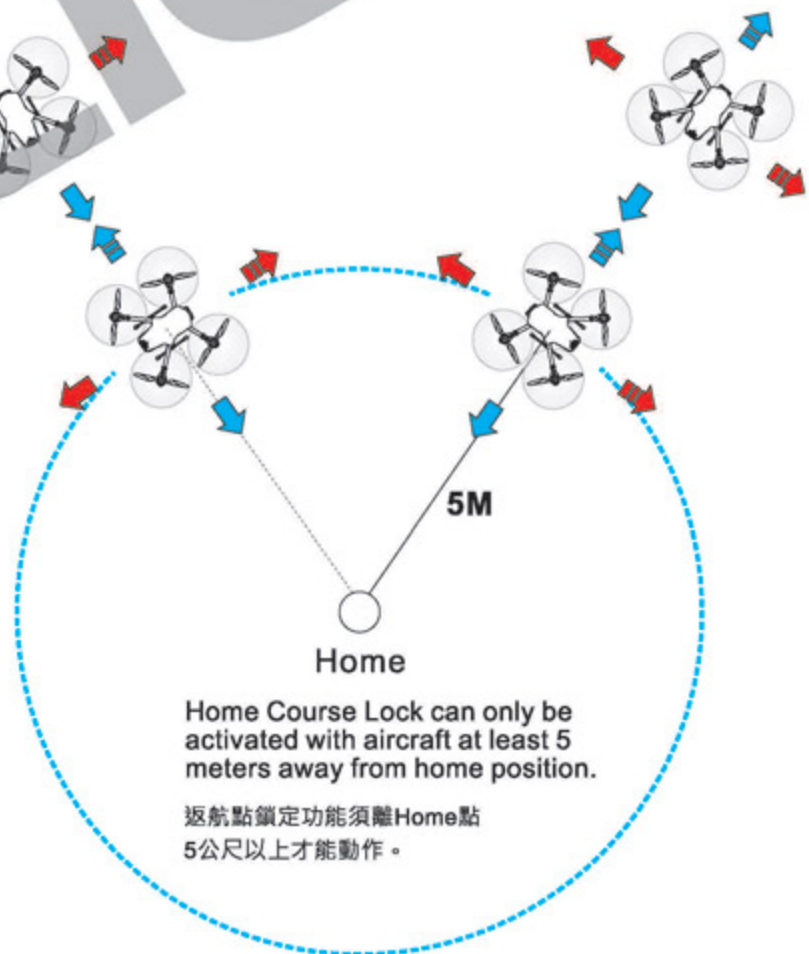
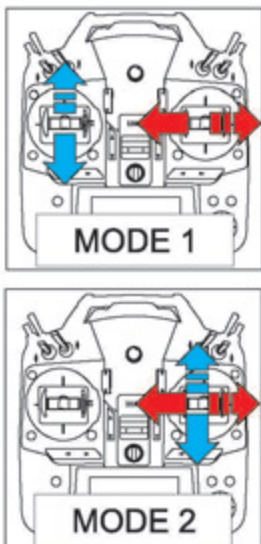
返航點鎖定只適用GPS速度模式，手動、姿態模式不支援返航點鎖定。

Home course lock utilizes the home position as base point. Pushing elevator stick back will force the multicopter to fly toward the home position regardless of its current heading, and pushing elevator stick forward will force it to fly away from home position.

1. When this function is active and multicopter returns home, once it reaches the 5 meters point from home, APS-M will put the multicopter into hover, and lock out elevator/aileron/rudder control. At this time throttle can be used to land the multicopter, or Home Course Lock can be disengaged for manual landing.
2. Please confirm home position during power up.

返航點鎖定是以Home點位置為基準，不論飛行中的機頭朝向為何，控制的頭向是以Home點朝向多軸機位置的方向呈十字航道控制模式，當升降往後打時，多軸機不論頭向朝Home點飛回，升降往前打時，多軸機則往外飛離。

- 1.當開啓此功能將多軸機飛回Home，多軸機回航至離Home點5公尺時，APS-M會將多軸機停止至該位置，並鎖定升降、副翼、尾舵動作，此時可控制油門將多軸機降落，或是解除返航點鎖定使用手動降落。
- 2.請務必確認開機時Home點位置。



3 CFO(CAREFREE ORIENTATION) 航向鎖定

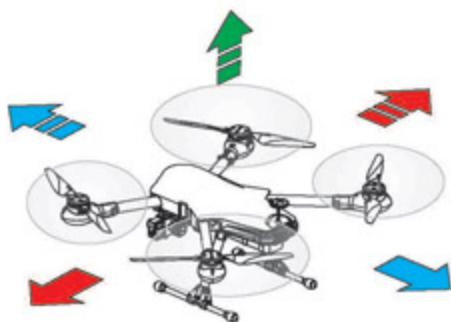
ATTITUDE & GPS

Carefree Orientation Mode is suitable only under attitude and GPS Velocity mode. It is not supported under manual mode.

航向鎖定只適用姿態和GPS速度模式，手動模式不支援航向鎖定指令。

While in CFO (Carefree Orientation) mode, any control command direction will be based on the initial direction of multicopter during power up, regardless of which direction it's currently pointing. The aircraft will fly right with right aileron stick input, and fly left with left aileron stick input, regardless of the current heading. While in CFO Mode, multicopter will be in attitude/altitude mode, with stick control translated as angular command.

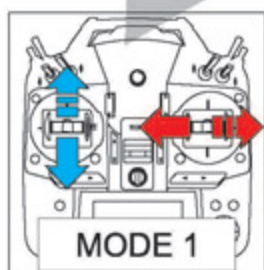
航向鎖定是以開機時的機體頭向做為基準，不論飛行中的頭向為何，開啓此模式時飛行機會以開機時的頭向為基準，當副翼向右打時，飛行機則向右飛；副翼向左打時，飛行機則向左飛，與遙控器動作相同。航向鎖定功能，多軸機為姿態水平與定高功能，搖桿指令為角度命令。



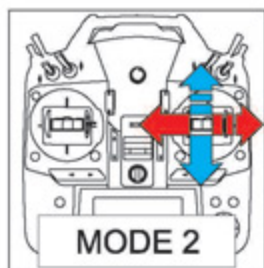
CAUTION
注意

Please confirm home position and heading position during power up.

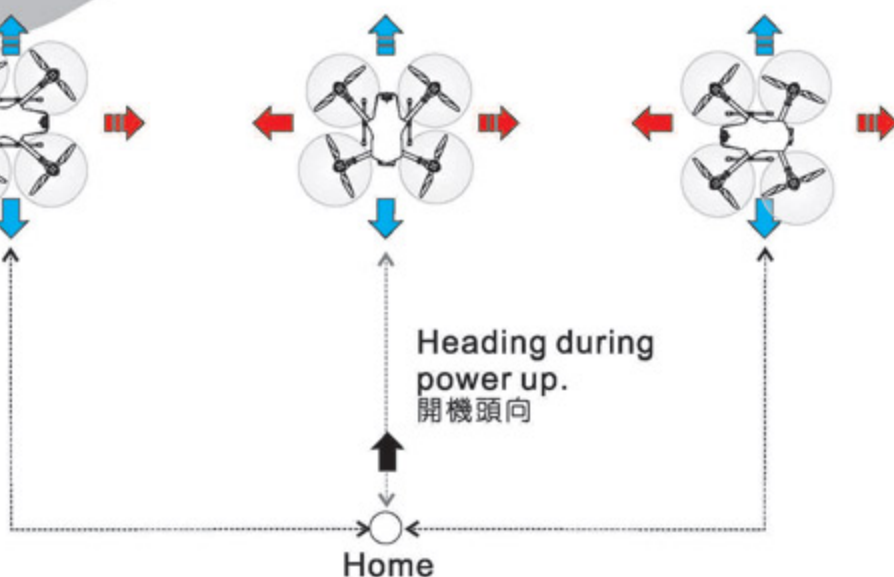
請務必確定開機時Home點位置及開機頭向



MODE 1



MODE 2

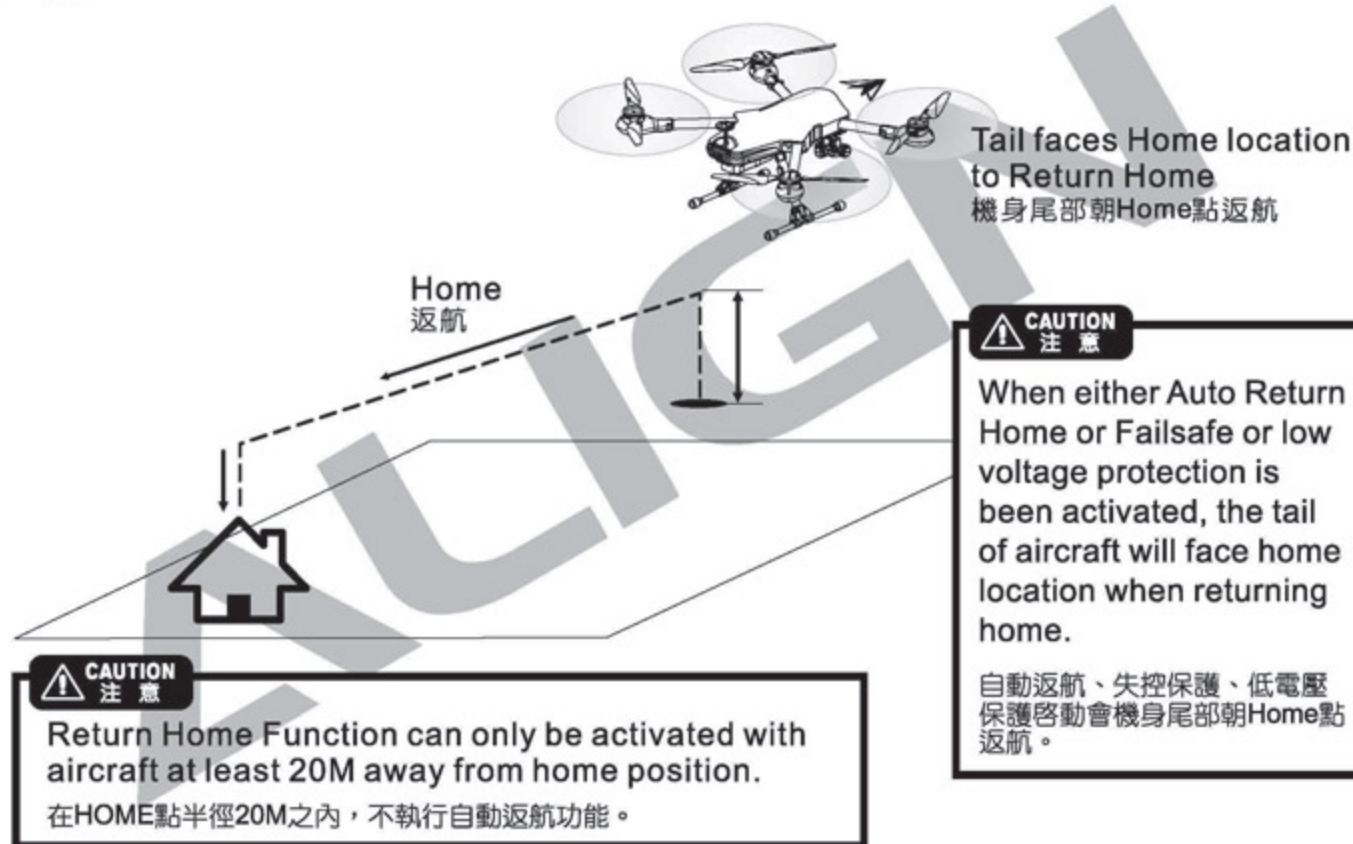


Automatic return home can only be activated under attitude and GPS mode; it is not supported under manual mode.

自動返航只適用姿態和GPS模式，手動模式不支援自動返航指令。

Automatic return home function is a flight aid in scenario where the pilot has lost sight of the aircraft, or is unable to tell its orientation due to excessive distance, the aircraft will automatically and securely fly back to the home position under GPS mode with good GPS satellite reception.

自動返航功能是輔助多軸飛行機在操控過程中，若發生迷航或距離太遠無法辨識正確飛行方向時，在GPS模式下且衛星訊號良好的狀態下，可藉由飛控系統執行自動返航指令，讓多軸飛行器在安全機制下自動駕駛安全返回Home點。



TO ENGAGE AUTO RETURN HOME COMMAND
開啓自動返航指令



Toggle the Return Home switch to ON position
將自動返航開關切入開啓位置

TO DISENGAGE AUTO RETURN HOME COMMAND
解除自動返航指令



Toggle the Return Home switch to OFF position
將自動返航開關切回關閉位置

1. Home Position: When GPS signal is first received after power on, the mode LED will flash rapid green to indicate home position has been recorded.
2. Return Home Method: Regardless of current position, when Return Home is activated, multicopter will rise, rotate until the rear points toward home position, then proceed to fly toward home position. If retracts are in the up position, APS-M will lower the retractable landing gears down, then proceed to land at the home location.

1. Home點：開機後，第一次收到GPS訊號的位置，此時模式燈會快速閃爍綠燈表示以記錄Home點位置。
2. 返航方式：無論在什麼位置，飛行中如果開啟自動返航功能，多軸飛行機會先自動上升再轉動尾部朝向Home點，然後飛回Home上方，如果飛行機有收腳架，此時APS-M會把腳架放下，然後降落在Home點位置。

 CAUTION
注意

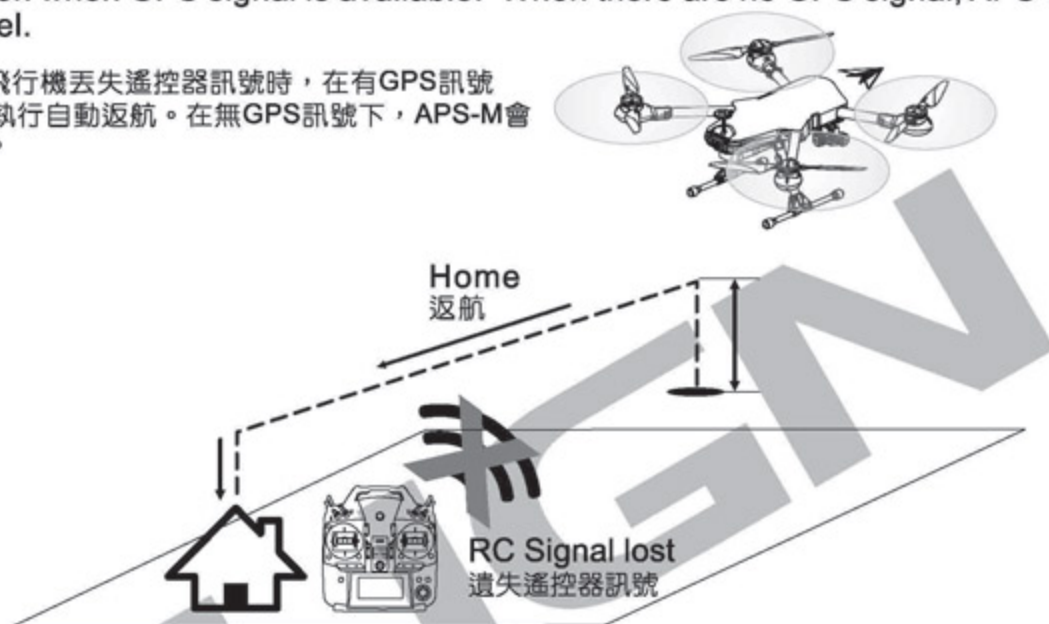
1. During automatic Return Home function, multicopter will choose the shortest path between current location and home location, flying with multicopter's tail pointing at the pilot.
 2. If the flight path deviates from the intended path to home during return home function, immediately disengage auto return home function, and manually fly the aircraft back home.
 3. If automatic Return Home function needs to be disengaged while returning home, flip the Return Home switch on and off to regain manual control.
1. 執行自動返航功能時，多軸機會從飛行位置與Home點最短的距離做為飛行路徑，以機尾方向朝操作者返航。
 2. 若在飛行機抵達Home點或返航途中，發生衛星定位回Home點航線偏移，請立即解除自動返航指令，以手動操控回Home點。
 3. 解除自動返航指令：把自動返航開關切回關閉位置，即能解除自動返航指令改由手動操作。

Failsafe Protection is only active under attitude and GPS mode; it is not supported under manual mode.

失控保護只適用姿態和GPS模式，手動模式不支援失控保護指令。

Failsafe Protection : When multicopter loses radio control signal, APS-M will initiate Return Home function when GPS signal is available. When there are no GPS signal, APS-M will maintain level.

失控保護：當飛行機丟失遙控器訊號時，在有GPS訊號下，APS-M會執行自動返航。在無GPS訊號下，APS-M會保持姿態水平。



TO DISENGAGE AUTO RETURN HOME COMMAND

解除自動返航指令

Return Home Switch to ON position
and immediately switch it to OFF
自動返航開關切入開啓再切回關閉位置



CAUTION 注意

1. Failsafe Protection is for use while in attitude and GPS mode only. Failsafe auto return home is not available in manual mode.
2. Should the RC transmitter signal is lost, APS-M will activate Failsafe Protection function to automatically fly the aircraft back home.
3. If failsafe auto return home function need to be disengaged while en route to home position, switch on Return Home mode and immediately switch it off, then control of multicopter can be regained.

1. 失控保護只適用於姿態模式與GPS模式下，手動模式無失控保護自動返航。
2. 當遙控器失去訊號無法控制時，APS-M會開啓失控保護功能，使多軸機自動返航至Home點。
3. 若在抵達Home點或返航途中需解除失控保護指令，只要把自動返航開關切入開啓再切回關閉位置，即能回復手動操控多軸飛行機。

Low voltage protection is only active under attitude and GPS mode; it is not supported under manual mode.

低電壓保護只適用姿態和GPS模式，手動模式不支援低電壓保護指令。

APS-M provides two methods for low voltage protection. Please refer to page 42 in the APS-M instruction manual for low voltage cutoff parameters.

1. First Stage Protection : low voltage warning light

Low voltage warning light: Sets the trigger voltage for low voltage warning. Recommended value is 3.625V, at which point the aircraft will have approximately 200M range left (around 1 minute). When voltage drops below the set value, APS-M LED will be flashing red.

2. Second Stage Protection : low voltage trigger for automatic go home

Low voltage Return Home : Sets the trigger voltage for low voltage return home. We highly recommend the value of 3.60V to be used, at which point the aircraft will have approximately 100M range left (around 30 seconds). When voltage drops below the set value, APS-M will initiate automatic return home feature.

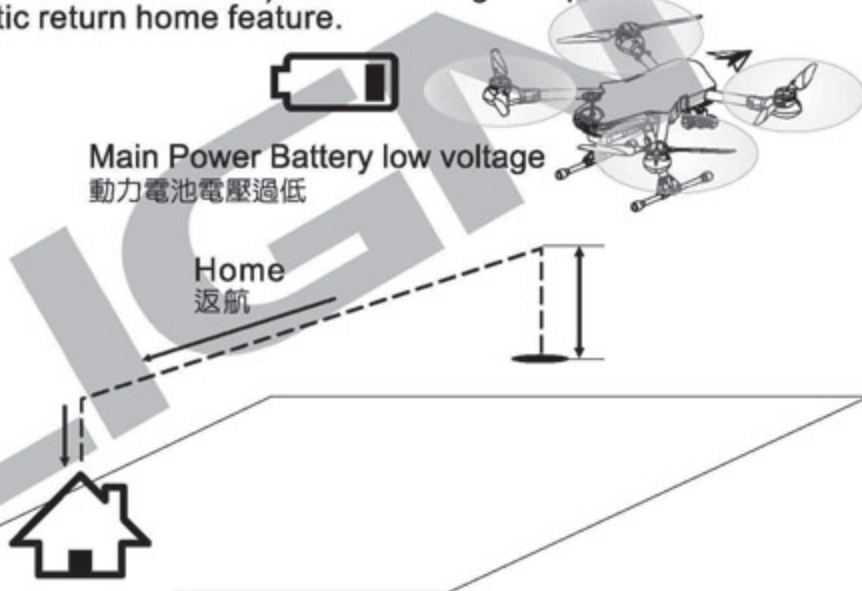
APS-M提供兩種低電壓保護，請參考APS-M操作介面安裝與設定第42頁，進行低電壓保護數據設定。

1. 第一階保護：低電壓警示閃燈

設定低電壓警示閃燈電壓，出廠設定為3.625V(建議值)，此電壓預估可安全飛行距離能力為(約1分鐘)200M，當飛行中電池電壓低於此設定電壓時，APS-M即會閃爍紅燈提醒。

2. 第二階保護：低電壓自動返航

設定低電壓自動返航電壓，出廠設定為3.60V(建議值)，此電壓預估可安全飛行距離能力為(約30秒)100M，當飛行中電池電壓低於此設定電壓時，APS-M即會執行自動返航。



TO DISENGAGE AUTO RETURN HOME COMMAND

解除自動返航指令

Return Home Switch to ON position and immediately switch it to OFF
自動返航開關切入開啓再切回關閉位置



Return Home OFF
自動返航關閉

Return Home ON
自動返航開啟

CAUTION 注意

1. We highly recommend activating low voltage protection function to ensure the safety of aircraft.
2. When executing return home function, the aircraft will automatically lower its retractable landing gears after reaching the home position.
3. To disengage auto return home command: Switch on Return Home mode and immediately switch it off, then control of multicopter can be regained.

1. 強烈建議開啓低電壓保護功能，提供飛行機安全保護。
2. 在執行自動返航動作時，當飛行機返回至Home點上方會自動放下腳架，準備降落。
3. 解除自動返航指令：先把自動返航開關切入開啓再切回關閉位置，即能解除自動返航指令改由手動操作。

SPECIFICATIONS

產品規格

ALIGN

APS-M Multicopter Control Unit APS-M多軸飛控系統

Input Voltage 輸入電壓	DC4.5V~8.4V
Operating Current Consumption 消耗電流	<250mA@ 4.8V
Operating Frequency 工作頻率	400Hz
Operating Temperature 工作溫度	-20°C ~ 65°C(-4°F ~ 149°F)
Hovering Precision (Depending on Satellite Status) 停懸精度 (受衛星狀況影響)	Horizontal ±1m(3.28ft), Vertical ±1m(3.28ft) 水平 ±1公尺, 垂直 ±1公尺
Maximum Flight Speed 最大飛行速度	Horizontal 15m/sec, Vertical 6m/sec 水平 15公尺/秒, 垂直 6公尺/秒
Maximum Altitude Restriction 飛行高度限制	700m(2297ft) above the takeoff point 距起飛點上方700公尺
Maximum Angular Speed 最大角速度	Aileron/Elevator 115°/sec, Rudder 145°/sec 副翼/升降 115度/秒, 尾舵 145度/秒
Maximum Tilting Angle 最大傾斜角度	30 degrees 30度
Supports External Peripherals 支援外接產品	G2/G3 Gimbal, OSD+FPV Video Transmitter G2/G3雲台, OSD+FPV影像發射器
Supports Multicopter Configurations 支援機型	4 rotors+, 4 rotors X, 6 rotors+, 6 rotors X, 8 rotors+, 8 rotors X. 四軸+型、四軸X型、六軸+型、六軸X型、八軸+型、八軸X型
Dimension 尺寸	49x34.3x20mm

PCU Power Control Unit PCU電源控制組

Input Voltage 輸入電壓	13.2V~25.2V(4S~6S Li-Po)
Operating Frequency 工作頻率	500KHz
Dimension 尺寸	62x35x26mm
Operating Temperature 工作溫度	-5°C ~ 45°C(23°F ~ 113°F)

Multicopter Brushless ESC 多軸無刷調速器

Input Voltage 輸入電壓	13.2V~25.2V(4S~6S Li-Po)
Max Continuous Current 最大持續耐電流	40A
Dimension 尺寸	74.2x27x12.7mm
Operating Temperature 工作溫度	-5°C ~ 45°C(23°F ~ 113°F)

RCM-BL4213 Brushless Motor 370 KV (RPM/V) RCM-BL4213無刷馬達 370KV(RPM/V)

Input Voltage 輸入電壓	DC 22.2V	Stator Arms 矽鋼片槽數	12
Max Continuous Current 最大持續耐電流	25A	Magnet Poles 磁鐵極數	14
Max Continuous Power 最大持續功率	550W	Dimension/ Weight 尺寸/重量	φ 4x φ 52x33mm/ 185g

G2 GIMBAL G2雲台

Input Voltage 輸入電壓	DC 12V(3S)
Operating Current Consumption 消耗電流	<500 mA@12V
Maximum Control Range 最大可控制範圍	PAN360°, ROLL±20°, TILT120° 指向360度/秒, 滾轉±20度, 俯仰120度
Maximum Control Rotation Rate 最大可控制旋轉速度	PAN60°/sec, ROLL60°/sec, TILT60°/sec 指向60度/秒, 滾轉60度/秒, 俯仰60度/秒
Temperature Range 工作環境溫度	-20~80 degrees -20~80度
Voltage Output 接收器輸出	5V / 0.3A
Dimension 尺寸	100.4x74x111.5mm

Q&A 1

Unable to Power On?

- (1) Press power button momentarily to check remaining battery level.
- (2) Check if battery plug is connected properly.
- (3) Check for proper connection between APS-M and PCU.

無法正常開機?

- (1) 短按電源指示燈的電源鍵檢查電池剩餘電量。
- (2) 檢查電池接頭是否沒有接好?
- (3) PCU電源控制組與APS-M多軸飛控系統之間連線是否沒有接好?

Q&A 2

APS-M will not start up after power up?

- (1) Check for any abnormalities in power source. Verify connection between APS-M/PCU/Receiver are correctly connected.
- (2) Check for correct receiver type selection in configuration interface.
- (3) NOTE: APS-M must remain stationary, and will start properly only after system initialization is completed.

APS-M開機後，APS-M無法啟動?

- (1) 檢查系統電源是否正常，APS-M與PCU、接收器之間連線是否正確連接。
- (2) 檢查操作介面的接收器類型是否正確。
- (3) 注意APS-M啟動時機體必須保持靜止，當系統開機初始化完成後才會正常啟動。

Q&A 3

Long GPS acquisition time? Wide variance during position hold?

- (1) Initial acquisition time will be longer for first time power ups.
- (2) Satellite signal will be weaker in urban area with highrise or other obstacles. Ideal location should be an open field free of magnetic interferences.
- (3) If 7 or less satellites were acquired, LED warning light will be displayed and GPS functions will not activate.
- (4) Please refer to the satellite acquisition table on page 57 to determine satellite reception status.

為何搜尋GPS時間長?定位偏移大?

- (1) 首次開機衛星接收時間一般會較長，屬正常現象。
- (2) 在市區大樓有遮蔽物地點，衛星訊號較弱；建議遠離強磁和導磁在空曠地使用，衛星訊號會較強。
- (3) 衛星數低於7顆時，LED燈會顯示無衛星訊號，GPS功能不會開啓。
- (4) 請參考P57磁力計校正/衛星訊號接收表，來判定您的衛星訊號接收狀況。

Q&A 4

Motor spins the wrong direction during motor spin test?

Connection between motor and ESC did not follow proper color coding, or direction switch on ESC set incorrectly.

為何馬達測試運轉時，馬達轉向錯誤?

馬達與電子變速器之間接線沒依照顏色連接，或電變設定馬達轉向開關設定錯誤。

Q&A 5

Motor did not follow M1/M2/M3/M4 sequence during motor test?

Check the ESC signal wires are connected to correct ports on APS-M.

馬達測試運轉時，馬達沒依照M1、M2、M3、M4順序轉動?

檢查電子變速器訊號線與APS-M之間接線，是否有照順序連接。

Q&A 6

APS-M powered up properly, but will not fly after performing the startup stick sequence?

- (1) Check and ensure D/R (Dual Rate) function is not configured on transmitter.
- (2) Check if stick calibration was done. Go to the configuration program and run the stick calibration again.

APS-M有正常開機，但無法搖桿解鎖起飛?

- (1) 檢查遙控器是否有設定D/R，使用APS-M不可設定D/R功能。
- (2) 檢查遙控器是否有執行搖桿校正，重新至操作介面設定搖桿校正。

Q&A 7

Airframe tilts forward or backwards during takeoff?

Check for proper balance on CG point. Adjust the battery or gimbal position to achieve proper CG balance.

起飛時會有後傾或前傾現象?

檢查機體重心是否正確，請調整電池、雲台位置，使重心落在機體中心點位置。

Q&A 8

Airframe fails to stay in one spot during pirouetting maneuver (spin of airframe with rudder applied)?

- (1) Check for proper APS-M Multicopter GPS Sensor location configuration in configuration program.
- (2) Check for proper balance on CG point. Adjust the battery or gimbal position to achieve proper CG balance.

打尾舵自旋動作，無法在固定點旋轉?

- (1) 檢查操作介面的APS-M多軸GPS感應器設定是否正確。
- (2) 檢查機體重心是否正確，請調整電池、雲台位置，使重心落在機體中心點位置。

Q&A 9

Airframe experiences slow response during flight, and drifts as if it's not holding position?

Increase the gain value under attitude mode.

飛行時動作反應較慢，會有飄移鎖不住的現象？
建議將姿態模式敏感度增加。

Q&A 10 Excessive or insufficient stopping power during while flying?
Adjust the stopping power parameter in program interface to increase or decrease accordingly.
空中飛行停止制動力過強或過弱？
調整介面GPS制動感度，制動力過強，降低感度；制動力過弱，增加感度。

Q&A 11 Slight left/right shakes of video footage or aircraft heading during flight or hover ?
Increase the rudder gain value under manual and attitude mode.
飛行或停懸時，頭向或拍攝畫面微量左右晃動？
將手動模式及姿態模式尾舵感度增加。

Q&A 12 Unable to hold position for vertical climb in GPS mode?
Increase the elevator and aileron gain under attitude and GPS modes.
GPS模式下無法定點垂直爬升？
調高姿態/GPS的升降、副翼感度。

Q&A 13 Motor and Navigation lights do not turn on?
(1)Check if signal wire from motor arm assembly is plugged in backwards.
(2)Open the motor mounting pod to see if ESC signal wire is detached.
馬達及飛行指示燈無法啟動？
(1)檢查馬達訊號線是否反插。
(2)拆開馬達固定座，檢查ESC訊號線是否脫落。

Q&A 14 Gimbal status LED does not light up, or gimbal does not have any movement.
Check power is connected to gimbal, and also ensure power cable between PCU and gimbal is properly connected.
雲台指示燈不亮或無動作反應。
檢查雲台是否有供電，PCU與雲台之間電源線是否有正確連接。

Q&A 15 Recorded video has wavy lines (jello effect)
(1)Check for excessive vibration on airframe and eliminate the vibration source.
(2)Use an appropriate damper.
(3)Check if gimbal motors are oscillating, then lower the P gain and Power values.
雲台拍攝畫面有水波影像。
(1)檢查機體是否有過大震動，且排除震動源。
(2)選擇正確雲台避震墊圈使用。
(3)檢查雲台馬達是否有抖動情況，可降低該軸馬達P感度與Power。

Q&A 16 Recorded video has slight swaying movement
(1)Multicopter rudder gain is too low; increase the rudder gain in both Manual and Attitude modes.
(2)The P gain and Power value are too low for gimbal's Pan axis. Increase these values.
雲台拍攝畫面微幅左右晃動。
(1)多軸飛行機尾舵感度偏低，請將手動模式與姿態模式的尾舵感度提高。
(2)雲台Pan軸P感度與Power偏低，將感度提高。

Q&A 17 Motor(s) exhibit high frequency oscillation after gimbal powers up.
(1)Ensure gimbal CG is balanced correctly.
(2)Lower the oscillating motor's P gain and Power values. Lighter cameras requires lower values.
雲台開機後，馬達出現高頻振動。
(1)請先確認雲台重心是否調整正確。
(2)降低該震動馬達的P感度與Power，相機越輕感度要較低。

Q&A 18 Gimbal exhibits momentary pauses while compensating.
Adjust the gimbal heading of affecting axis, and increase the P gain and Power value for this specific axis
雲台修正時，出現一格一格停頓現象。
調整會有該現象的雲台軸向，將該軸P感度與Power加大。

Q&A 19 Oscillation when gimbal points the camera straight down.
(1)Ensure gimbal CG is balanced correctly.
(2)Lower the P gain and Power values on gimbal's Roll axis.
將雲台相機朝下時，會出現抖動情況。
(1)請先確認雲台重心是否調整正確。
(2)將雲台Roll軸的P感度與Power降低。

Q&A 20 Recorded video has lateral or vertical unstable movement?
Gimbal compensation is too slow. If the video has lateral unstable movement, please increase the P gain values on gimbal's Roll axis. If the video has vertical unstable movement, please increase the P gain values on gimbal's Tilt axis.
拍攝畫面會有水平左右或上下不安定晃動情況？
雲台修正速度過慢，畫面水平左右晃動，請將Roll軸P感度調高；畫面上下晃動，請將Tilt軸P感度調高。

ALIGN

Specifications & Equipment/規格配備:

Airframe Diameter/軸距:710mm

Main Blade Length/主旋翼長:179mm

Main Rotor Diameter/主旋翼直徑:391mm

Height/機身高:266mm

Flying Weight(without battery)/全配重(不含電池): Approx. 2500g

