Telemetry

For now, all versions supporting Telemetry for Devo plus Devo .dfus in This RCGroups Post

Devo 7e update info:

The telemetry is present in deviation firmware in the latest nightlies, currently. That means you may need to flash a recent nightly to make use of telemetry with the bayang protocol, and your flashed quadcopter.

Please back-up the model files, and perhaps other files just in case, when upgrading the transmitter firmware.

To enable telemetry , hit enter when selecting bayang protocol, the same as enabling telemetry for other protocols, such as DSMX

The protocol with telemetry enabled will **only bind to a quad with telemetry capability**. With telemetry off, it will bind to all quads, including factory firmware, and telemetry quads.

About telemetry data:

The quad sends battery voltage, battery voltage- compensated against throttle , packets received (reception quality indicator) , and battery low -led flash signal

Additionally, the tx generates telemetry reception stats.

Telemetry names:

***Fades_L** - led battery low flashing= 100 , otherwise 0
***Loss** - TX's telemetry reception quality indicator in packets per seconds (max 200)
***Holds** - quad's reception indicator in packets per seconds (max 200)
***RxV** -**Volt1**- real battery voltage
***Batt** -**Volt2**- compensated battery voltage

Alarms:
FadesL > 1 will create an alarm that sounds if the leds flash a low battery code
Batt ⇐ 3.40 is ok for low battery alarm - using voltage compensation settings from config.h
Rxv ⇐ 2.90 - real battery voltage - this would be more like a traditional lvc that sounds on max throttle sometimes

The real voltage goes down a lot, so it may not be very useful. An alarm of 2.8 - 3.0 could be used.

Additional:
Since the telemetry range is shorter compared to the tx range (with PA) , there is no point setting an alarm for quad reception strenght, as the telemetry will probably fail before that level is reached.

The quadcopter only sends telemetry after a packet is received from the transmitter. This is to avoid on-air clashes when the code hopping becomes unsyncronized. Because of this, the telemetry rate

will go down when reception is poor.

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