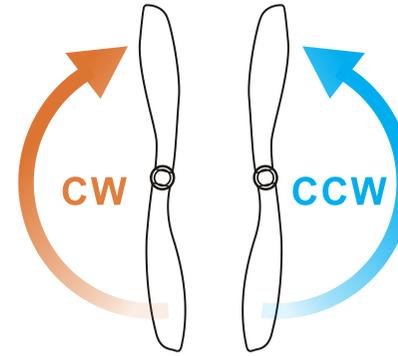
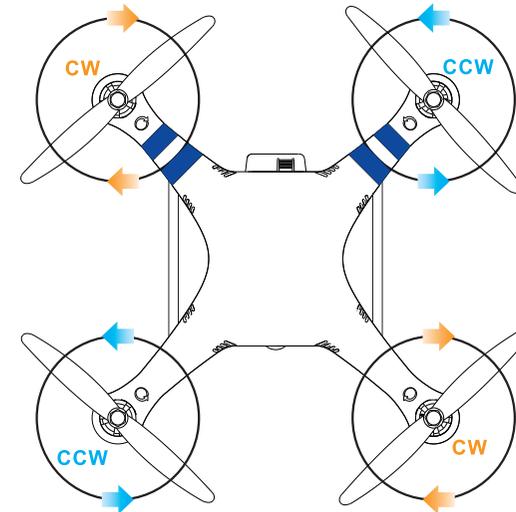


USER MANUAL

PROPELLER



Refer to the above illustration for information on how to determine correct propeller orientation. CW means clockwise, CCW means counterclockwise.



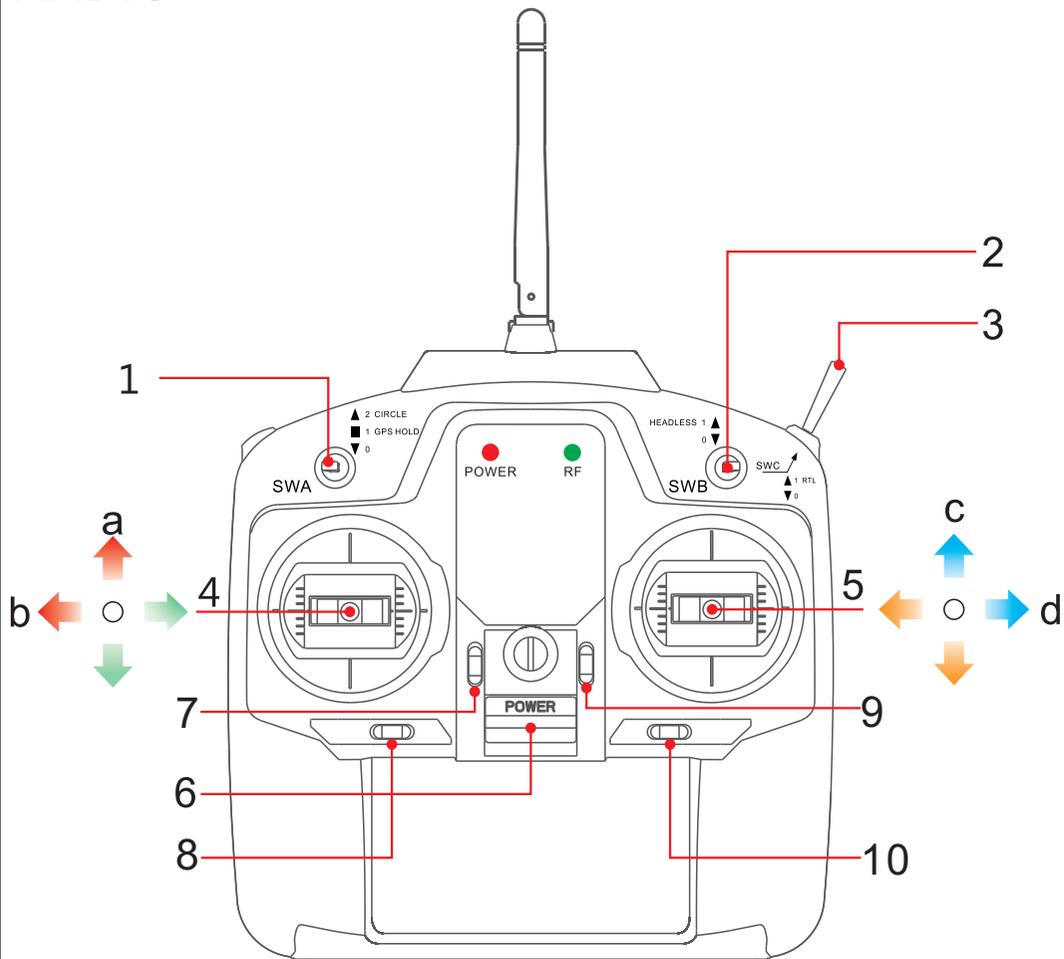
Install the propellers according to the picture above.

WARNING:

1. Be sure to not over tighten the propeller nuts, only tighten the nuts till the washer is slightly crushed. It is also recommended that you don't use excess force or Loctite when installing the propeller nuts.
2. Make sure you have the CW or CCW propellers installed on the correct motor.
3. The propellers have a somewhat sharp edge so it is advised to wear gloves when install the propellers to avoid injury to your hands.
4. Make sure that before every flight the propellers are installed correctly and securely. Do not get too close to the rotation of the blades and the motors to avoid personal injury.
5. Check whether all parts of the quadcopter are in good condition before flight. Do not fly with aging or broken parts.

6. Please only use the supplied propellers or the listed replacement propellers, we cannot guarantee the quality of other make's propellers as they could lead to unstable flight.

RADIO



1. Switch A (SWA): 0 Altitude Hold, 1 GPS Position Hold, 2 Circle Point of Interest (POI)
2. Switch B (SWB): 0 Normal, 1 Headless Mode
3. Switch C (SWC): 0 Normal, 1 Return to Location (RTL)
4. a-Throttle (Move up/down), b-Yaw (Rotate left/right)
5. c-Pitch (Move forward/backward), d-Roll (Move left/right)
6. Power Switch
- 7, 8, 9, 10. Factory default setting is set to the center, adjustment is not recommended

BASIC OPERATIONS GUIDE

Move the throttle stick to the middle position to hover.

◀ Indicates the forward direction of the quadcopter.

Radio	Quadcopter	Control Mode
		The left stick is for controlling the ascending and descending of the quadcopter, below 50% throttle the quadcopter will descend and above 50% throttle the quadcopter will ascend. Middle position will maintain the hovering of the quadcopter. Be sure to provide minor or slight inputs to the left stick or else the quadcopter will ascend or descend rapidly.
		Direction of the joystick is used to control the quadcopter's heading (yaw); the left stick's side to side movement will control the quadcopter's clockwise and counterclockwise rotation. Rotational speed is proportional to stick input on the transmitter.
		Direction of the joystick is used to control the quadcopter's left/right movement (roll). Movement speed is proportional to the stick input on the transmitter.
		Direction of the joystick is used to control the quadcopter's forward/backward movement (pitch). Movement speed is proportional to the stick input on the transmitter.
		Flight Mode Control Switch (SWA): SWA 0: Altitude Hold, quadcopter might drift in windy condition. SWA 1: GPS Position Hold. SWA 2: Circle Point of Interest (POI)
		Flight Orientation Mode (SWB): SWB 0: Normal. SWB 1: Headless.
		Control Switch C (SWC): SWC 0: Normal. SWC 1: Return to Location (RTL).

READY TO FLY

First Fly:

- A. Before flying the quadcopter it is recommended that you have prior experience with flying RC quadcopter, flight time under a RC flight simulator, or training under an expert's prevision.
- B. Do not fly the quadcopter in bad weather such as rain, snow, high wind (more than a moderate breeze), hail, lightning, tornadoes, hurricanes etc.
- C. It is recommended that you fly the quadcopter in an open field without tall buildings; concrete structures can interfere with the function of the compass. GPS signal will reflect off of buildings and can decrease the accuracy of the position of the quadcopter.
- D. Do not use the quadcopter in areas with high magnetic interference, or radio interference. This will cause communications errors between the quadcopter and transmitter or other failures.
- E. The GPS positioning system will not work in the Antarctic or Arctic circle since the compass will not receive an accurate reading.
- F. Consult with your local laws/authorizes regarding approved airspace, NEVER fly in unauthorized or commercial airspace.

1. Turn on the transmitter (ensure the SWA, SWB and SWC are on the zero position).
2. Place the quadcopter on a flat surface and connect the battery on the quadcopter. Do not move the quadcopter after connecting the battery. The red status light should flash rapidly when the quadcopter is calibrating the barometer and leveling. Any movement on the quadcopter at this time may lead to initialization failure.

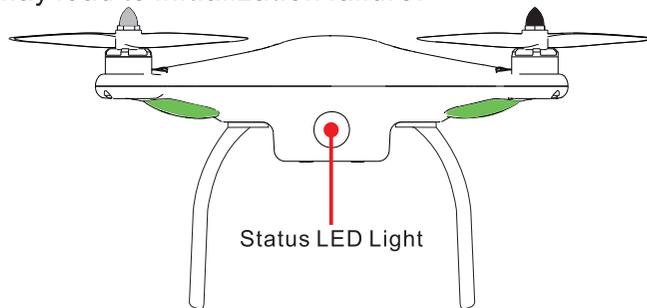


Figure 1

- QUADCOPTER STATUS LIGHT
- ● ● ● ● Quadcopter is unarmed (locked) when the red light is flashing.
- ▬ Quadcopter is armed (unlocked) when the red light is solid.

- GPS STATUS LIGHT
- ● ● ● ● GPS is not ready when the green light is flashing.
- ▬ GPS is ready when the green light is solid.

3. Please be patient and wait for the GPS status light to become solid green.
4. Make sure the rear end of the quadcopter faces you (status light is at the rear end of the quadcopter). Stay at least 20 feet away from the quadcopter.
5. **Unlock (arm) the quadcopter:** Ensure all the switches (SWA, SWB, SWC) are on the zero position. Move the left control stick to the lower right corner and hold it for about 5 seconds. The red status light should turn solid and propellers should start rotating in slow speed, this indicates the unlocking process is completed. Release the left control stick and move it back to the middle position slowly.
- Lock (disarm) the quadcopter:** Move the left control stick to the lower left corner and hold it for about 5 seconds. The red status light should start flashing and propellers should stop completely, this indicates the locking process is completed. Release the left control stick and move it back to the middle position slowly. The quadcopter should automatically disarm if the left control stick is left idle at the lowest position for 5 seconds.

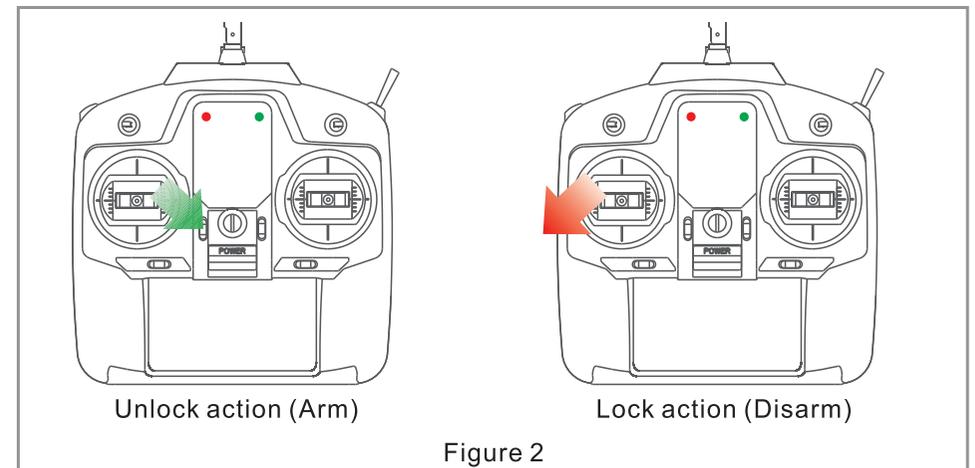
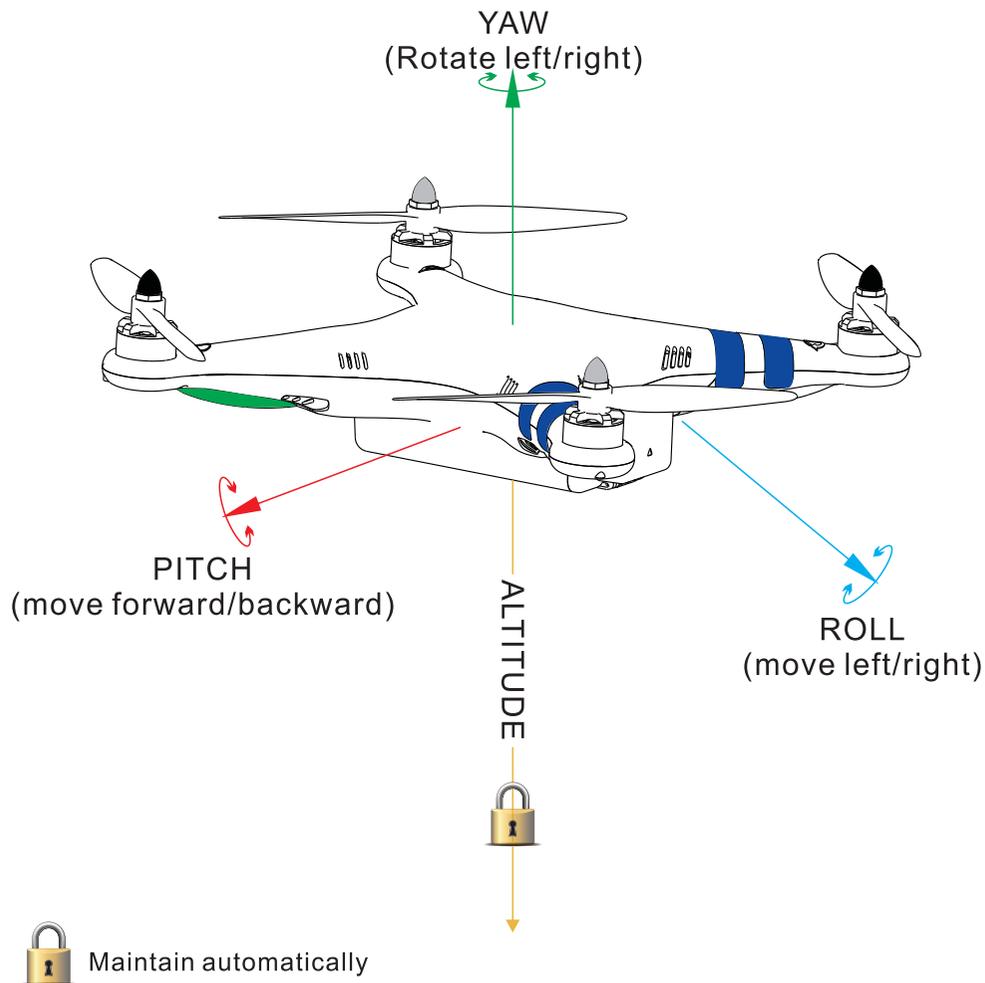


Figure 2

FLIGHT MODE

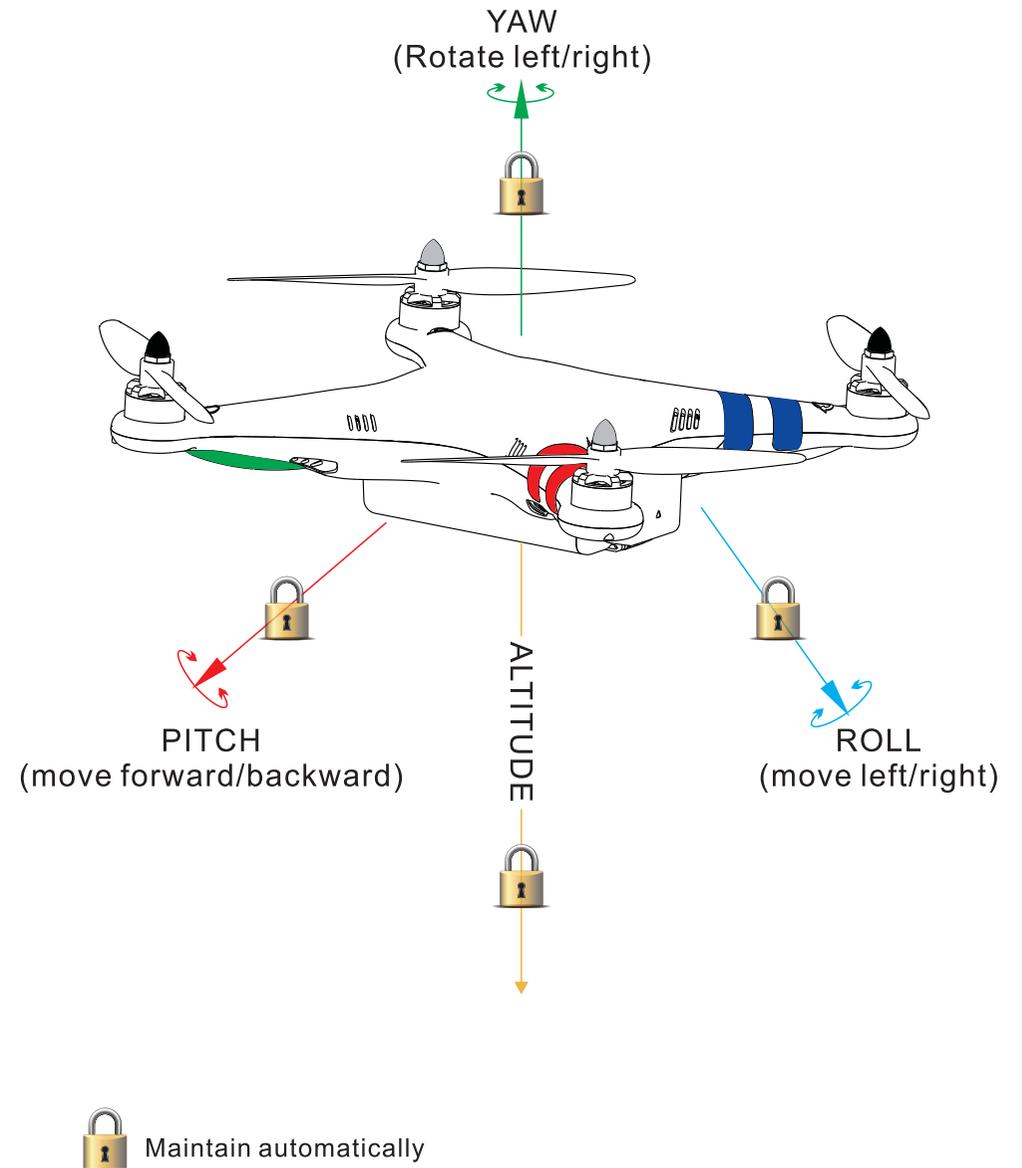
Stabilize (Altitude Hold) Mode (SWA 0)

The quadcopter automatically maintains the current height when the throttle stick is at the middle position. In stabilize mode, the quadcopter can achieve 10ft / sec amplitude correction. Maximum flying speed of 20mph. The quadcopter has to be at least 7ft off the ground to not to be affected by propeller wash from its airstream. Quadcopter may drift always from its position in windy condition in this mode.



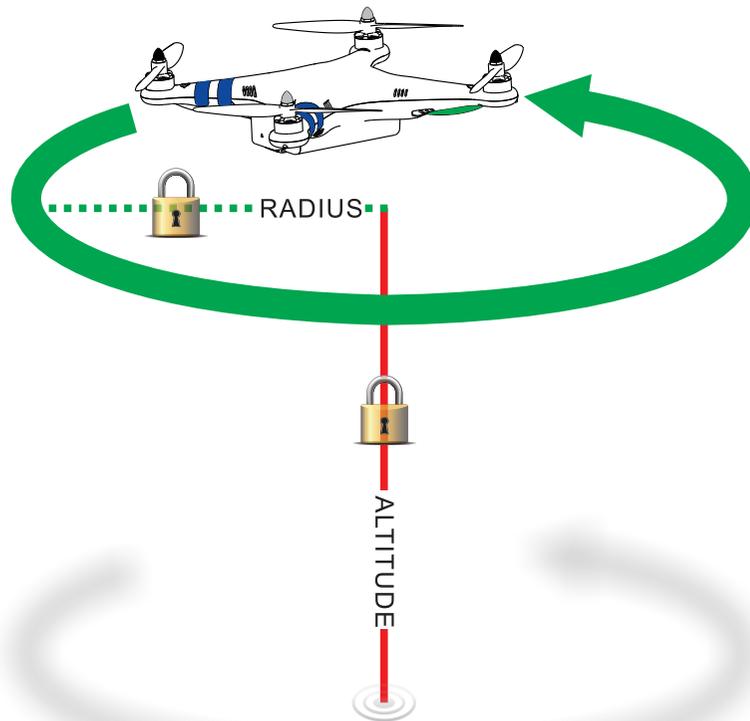
GPS Position Hold Mode (SWA 1)

In GPS hold mode, the quadcopter automatically maintains the current position, direction heading, and altitude. GPS lock is required for GPS position hold to function (green status LED light must be solid).



Point of Interest (POI) Mode (SWA 2)

In POI mode, the quadcopter orbits a point of interest with the nose of the quadcopter always points toward the center.



Quadcopter circulates a point of interest 30 feet always from the nose of the quadcopter when pilot starts the POI mode. (circle rate=20 deg/sec, radius =30 feet.)

Pilot does not have control on roll and pitch in POI mode.

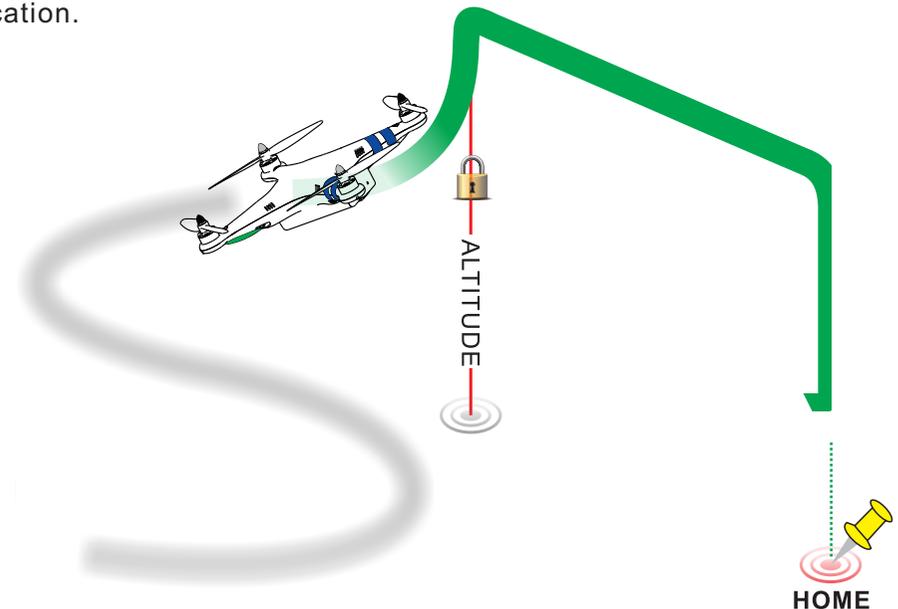
Return to Location (RTL) Mode (SWC 1)

RTL is GPS-dependent, so it is essential that GPS lock is acquired before attempting to use this mode. If GPS lock is acquired (green status LED light is solid) before arming the quadcopter, the home location is set to the arming location (recommended). If GPS lock is acquired after arming the quadcopter, the home location is set to the first acquired GPS location (not recommended).

This mode can be triggered by the following conditions:

1. Switch to the "1 RTL" position on switch C (SWC) on the transmitter.
2. Battery voltage on the quadcopter's battery is low (activate automatically).
3. Quadcopter fails to receive radio signal from the transmitter (activate automatically).

When RTL mode is engaged, the quadcopter should return to the home location. If quadcopter's current location is less than 7 feet always from the home location, quadcopter should land at the current location. Otherwise, the quadcopter should first rise up to 65ft before returning to home or it should maintain its current altitude if the current altitude is higher than 65ft. The quadcopter should automatically disarm after it lands at the home location.



Warning: In RTL mode, the flight controller uses a barometer which measures air pressure as the primary means for determining altitude (“Pressure Altitude”) and if the air pressure is changing in the flight area, the quadcopter will follow the air pressure change rather than the actual altitude.

If an obstacle is in the way of the quadcopter coming back to its takeoff location, you can exit the RTL mode and regain full control of the quadcopter in following methods.

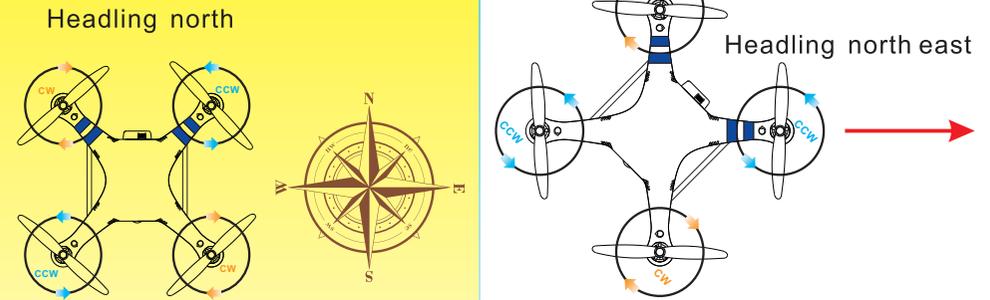
1. Change to any other new mode on switch A (SWA), the quadcopter should execute the mode action you just switch to on switch A.
2. Switch to the normal position on switch C (SWC), the quadcopter should execute the mode action currently on switch A (SWA)

If battery voltage on the quadcopter is low and GPS lock is not acquired, quadcopter should land on the current location slowly.

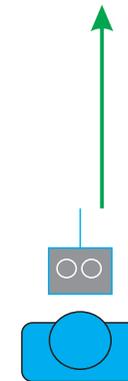
Headless Mode (SWB 1)

In headless mode, the control orientation is set based on the quadcopter's heading when armed. Headless mode is very useful when the quadcopter is too far away and it is difficult to determine its orientation.

Control orientation is set based on quadcopter's heading when armed. In this example, quadcopter is facing north when armed.

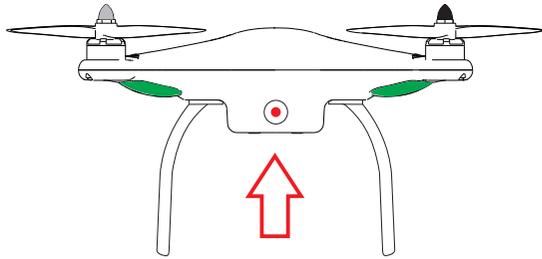


Pilot's forward command causes the quadcopter to move forward (north) regardless of the quadcopter's heading.

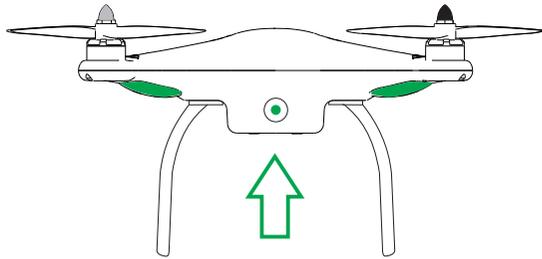


Pilot is facing north

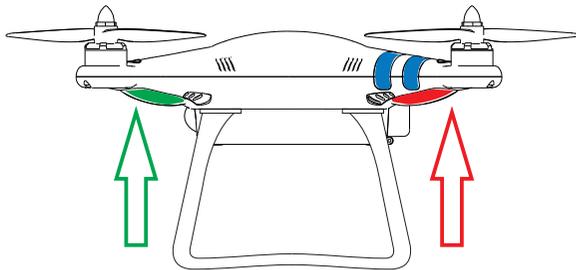
After connecting the battery on the quadcopter, the red status LED and the green GPS LED should flash rapidly for about 10 seconds. This indicates the quadcopter is initializing.



- ● When the quadcopter is disarmed (locked), the red status LED should flash once per second.
- When the quadcopter is armed and ready to fly (unlocked), the red status LED should be solid.



- ● When GPS lock is not acquired, the green GPS LED should flash once per second.
- When GPS lock is acquired, the green GPS LED should be solid.



- ● When the quadcopter is disarmed (locked), the status LEDs should flash once per second.
- When the quadcopter is armed and ready to fly (unlocked), the status LEDs should be solid.
- ● ● ● When the battery voltage on the quadcopter is low or the flight control on the quadcopter encounters error, the status LEDs should flash rapidly.

To avoid 2.4Ghz frequency signal interference between the Wi-Fi and the remote control receiver, do not turn on the Wi-Fi functionality on the camera after arming the quadcopter. You might lose control of the quadcopter due to frequency signal interference.

When interference happens, the quadcopter should execute the Return To Location (RTL) function automatically if GPS is acquired, or the quadcopter should land on the current location automatically if GPS is not acquired.

Letting the quadcopter to execute and finish the automatic recovery routine is recommended to avoid loss control of the quadcopter.

SAFETY WARNING

PLEASE READ CAREFULLY BEFORE FLIGHT!

1. The unit may crash as a result of improper use.
2. Do not exceed the mounted weight of our guidelines.
 - A. If you mount too heavy of an object on the quadcopter, the automatic control system may require more thrust than available, which could lead to instability.
3. Use of carbon fiber propellers isn't recommended with this unit for beginners.
 - A. It's recommended that you stick with the plastic propellers.
 - B. Carbon fiber blades are very strong, and will create deep lacerations if the blade strikes you.
4. If you fly the quadcopter near to other people, you would put them in danger!
 - A. Be sure to fly the unit away from yourself and people around you.
 - B. Adequate safe distance is necessary for a favorable flight.
 - C. Reference range: safe distance should be at least 20ft, and height of around 30ft.
 - D. Keep other people, property and obstacles farther away from the quadcopter.
 - E. Be sure that no one is between the quadcopter and you.
 - F. Audience should stay behind the pilot and maintain a safe distance.
 - G. If anyone steps into the area which you define as unsafe, please land the quadcopter right away and don't take off till they leave.
 - H. A fully charged quadcopter can travel to the speeds over 20mph (32km/h); it can also fly a few hundred ft. high and a few miles away.
5. Always make sure that the battery cable is not connected to the quadcopter until you are ready to take off.
 - A. Always keep the transmitter on while the battery is connected.
 - B. Disarm the quadcopter and disconnect the battery as soon as landing.
 - C. Do not turn the transmitter off until you disconnect the battery.
 - D. Take propellers off while testing motors.
 - H. Do not pick up the model and the remote control, as you might inadvertently unlock the quadcopter and operated the throttle stick.
 - I. Keep the flight time within the battery's safe capacity; reserve enough time for quadcopter return.
 - J. Don't try to fly the quadcopter more than recommended duration, you can risk overloading the battery, or the worst case will crash the quadcopter.
6. Arming and disarming the motors.
 - A. Connect the battery; keep the quadcopter stationary till the system self-check has finished. Move the left stick to the lower right corner of the controls. After arming the motors, if the left stick is left at the lowest position at idle, the motors will cut off after 5 seconds.
 - B. After landing the quadcopter, the motors will automatically disarm after 5 seconds if the left stick is left at the lowest position at idle. Disconnect the battery from the quadcopter if you're done with the flight.

7. Getting used to switching from other modes to stabilize mode.
 - A. You should practice on how to switch from other flight modes to stabilize mode.
 - B. Keep practicing in Stabilize mode until you've skilled.
 - C. Do not start using any other mode until you are well adapted to fly the quadcopter.
8. Important measures of crash, inadequate landing and unknown flight controller status.
 - A. In the event of a crash and being unable to disarm the motors you should put a towel on top of the quadcopter to shield yourself from the blades.
 - B. Disconnect the battery as soon as possible.
 - C. A large towel should be one of your most important safety equipment, only secondly to extinguisher and first-aid case.
9. Testing or flying under GPS mode
 - A. Make sure the GPS signal is stable before unlocking the unit and taking off.
 - B. There is a 15 ft of tolerance for the GPS lock on location. The most important conditions for the quadcopter are to receive most accurate GPS signal to return and land.

MOST IMPORTANT: Maintain a safe distance between the quadcopter from yourself and others. The following tips can protect your quadcopter from damage.

1. Avoid sudden or extreme operation on the controller.
 - A. Move the control stick gently and slowly, avoid any and all violent operation of the sticks.
 - B. Only fly the quadcopter if the unit has been calibrated and GPS positioning has been locked in, subtle and smooth operation of the sticks will lead to good height, direction and speed.
2. Your quadcopter should more or less keep a stable hover without any input on the control sticks.
 - A. In case of abnormal flight, land the unit immediately. Disconnect the battery and then connect it again; wait and do not move the quadcopter because it takes some time to reset gyro and barometer data.
3. Be careful while operating the throttle stick, make minor or little adjustments or

- else the quadcopter will ascend or descent rapidly.
4. Because quadcopter is symmetrical, it is easy to lose sight of orientation.
 - A. Under manual mode, it is critical to keep a clear view of the quadcopter's right opposite direction for a successful taking-off.
 - B. It is crucial, especially for beginner to maintain visual orientation of the quadcopter.
 - C. Usually, stand at least 20ft but at most 30ft away from the quadcopter.
 - D. If the quadcopter is over 100ft (30m) away, it becomes difficult to see orientation of the quadcopter, which will result in crashing the unit.
 - E. If you're flying in stabilize mode and don't know the direction of the quadcopter, just try to fly forward a little to regain reference.
 - F. If all possible it's best to descend and land the quadcopter to avoid crashing due to disorientation.
 - G. Disorientation happens sometimes, pilots sometimes reverse the direction of the quadcopter when they try to fly the quadcopter back causing it to go further out of sight range.
 - H. Consequently the quadcopter crashes far away, or get lost forever.
5. It's recommend that you always keep stabilize mode as a flight mode if you choose to reprogram the flight modes on the quadcopter.
6. Sudden high wind or gust will result in difficult flight.
 - A. Strong winds will prevent forward flight; which will cause you to be disoriented to the quadcopter.
 - B. The higher the altitude the increased risk of wind speeds may become.
 - C. Before you reach the limit of your ability to control the quadcopter switch over to stabilize mode and land the quadcopter, which can help you save your quadcopter.
 - D. Avoid flying too high or too fast, unless you have great confidence in your operation.
 - E. You are easily subjected to visual positioning failure, or even lose sight of quadcopter when you fly around trees or buildings.
 - F. High wind around large objects worsens the situation.
 - G. Radio signal lost is possible.
 - H. If your quadcopter is close to a potential obstacle, switch over to Stabilize mode immediately and land or get return the quadcopter you.
7. Safety features/modes: RTL (Return to Location), Fail Safe.
 - A. If the quadcopter starts to fly away you can enable RTL to return the quadcopter to the locked in location.
 - B. Set the Fail Safe against signal lost and if battery voltage drops below preset value (<10.7V Default value). Fail Safe will make the unit RTL or descend to save the quadcopter and reduce the chance of injuries.

- C. Do not totally rely on abovementioned safe modes. Always prepare to resume control over safe modes and land the quadcopter whenever necessary.
- D. Don't rely on safe mode for training exercises; and always consider the risks.
- E. These modes exist as a supplement, and should not replace safety practices.

8. Before flying

- A. Slowly increase the throttle in a stabilize mode until the quadcopter is hovering at about 4 ft height, release the throttle stick in the middle position.
- B. If rollover happens, turn off the quadcopter immediately and look for the cause.
- C. Motors may be rotating in the wrong direction.
- D. Propellers might be installed in the wrong direction.
- E. The quadcopter may turn around or out of control in certain direction.
- F. If the quadcopter tried to turn on flip it could mean one of the motors or ESC might not be operating correctly.
- G. The incorrect propeller was installed into the motor.
- H. When all the problems have been fixed, the quadcopter should easily hover 1ft to 2ft above the ground.

9. When flying FPV (First Person View)

- A. Make sure RTL works properly before flying FPV.
- B. If FPV video signal drops under stabilize mode, enable RTL mode to bring the quadcopter back to the locked in takeoff location.

10. Flying with camera that has Wi-Fi functionality.

- A. To avoid 2.4Ghz frequency signal interference between the Wi-Fi and the remote control receiver, do not turn on the Wi-Fi functionality on the camera after arming the quadcopter. You might lose control of the quadcopter due to frequency signal interference.**

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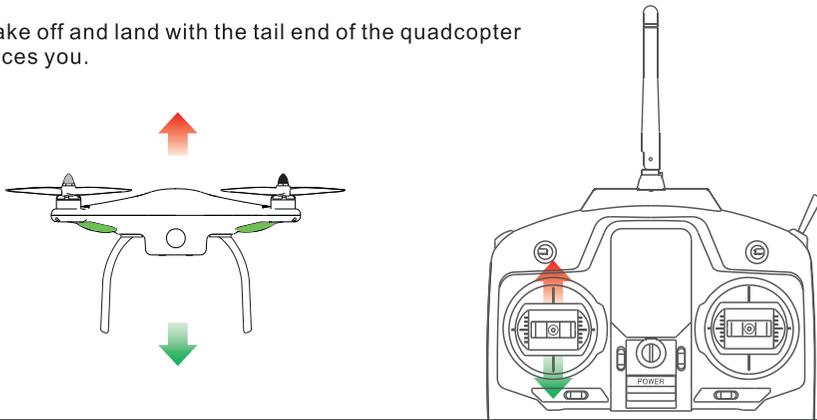
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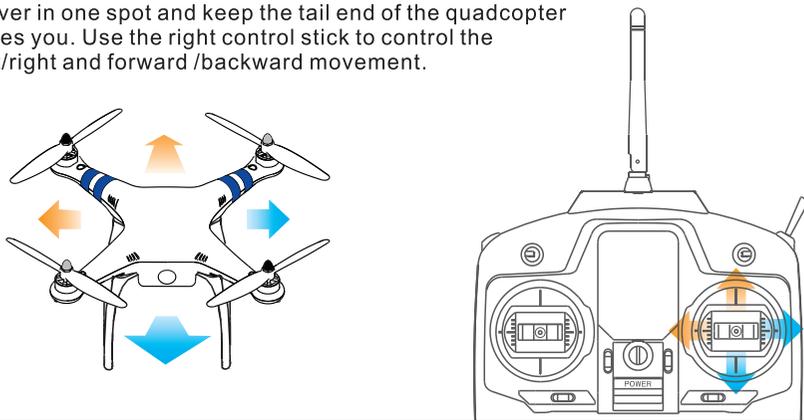
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Basic Flight Maneuvers

- 1** Take off and land with the tail end of the quadcopter faces you.



- 2** Hover in one spot and keep the tail end of the quadcopter faces you. Use the right control stick to control the left/right and forward/backward movement.

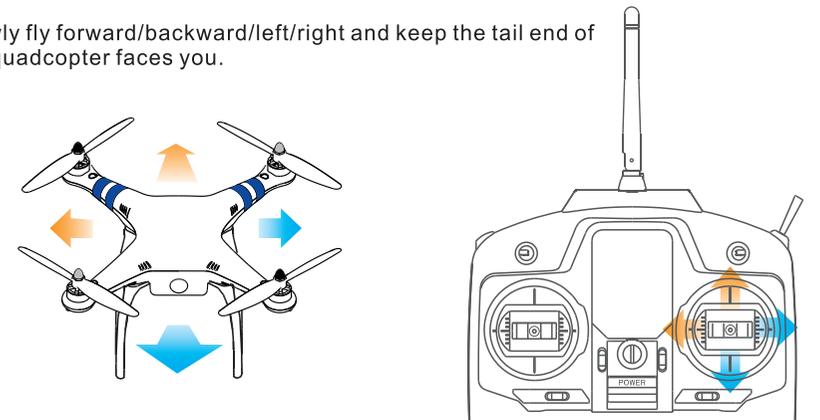


- 3** Rotate left and right slightly. Keep the tail end of the quadcopter faces you.

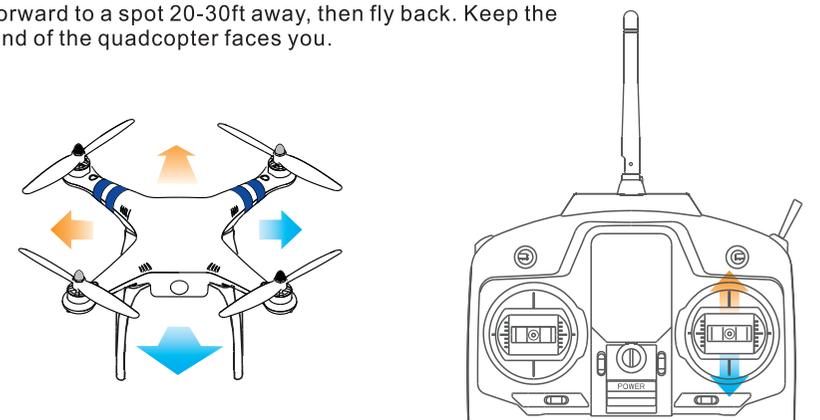


Basic Flight Maneuvers

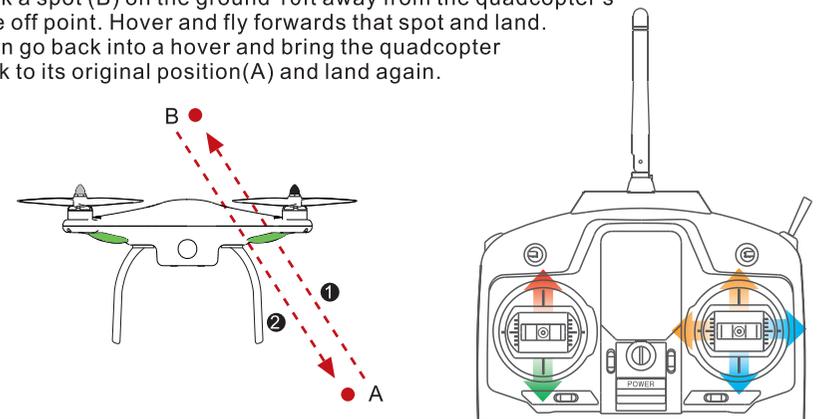
- 4** Slowly fly forward/backward/left/right and keep the tail end of the quadcopter faces you.



- 5** Fly forward to a spot 20-30ft away, then fly back. Keep the tail end of the quadcopter faces you.

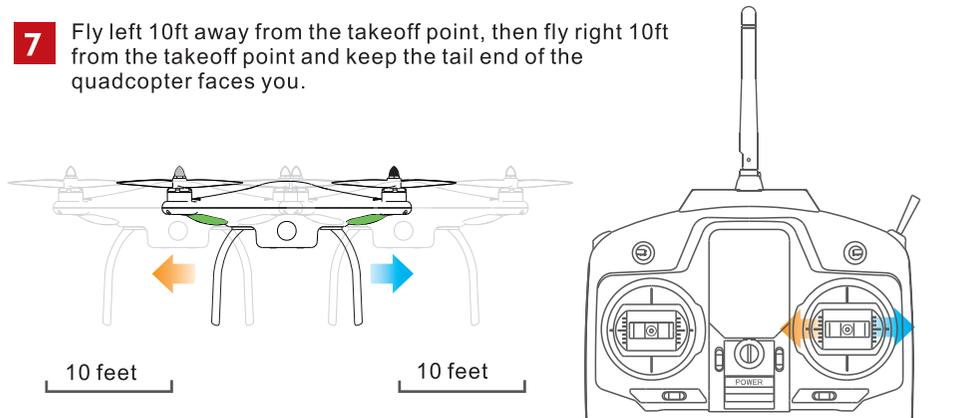


- 6** Mark a spot (B) on the ground 10ft away from the quadcopter's take off point. Hover and fly forwards that spot and land. Then go back into a hover and bring the quadcopter back to its original position(A) and land again.

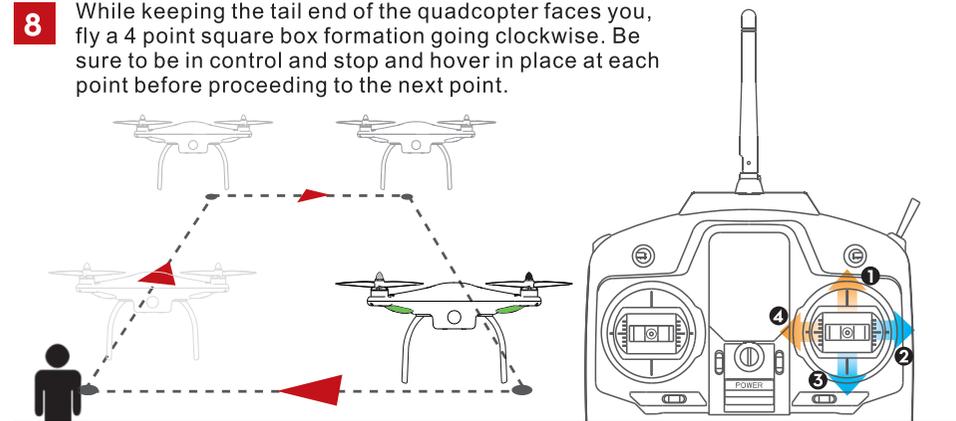


Basic Flight Maneuvers

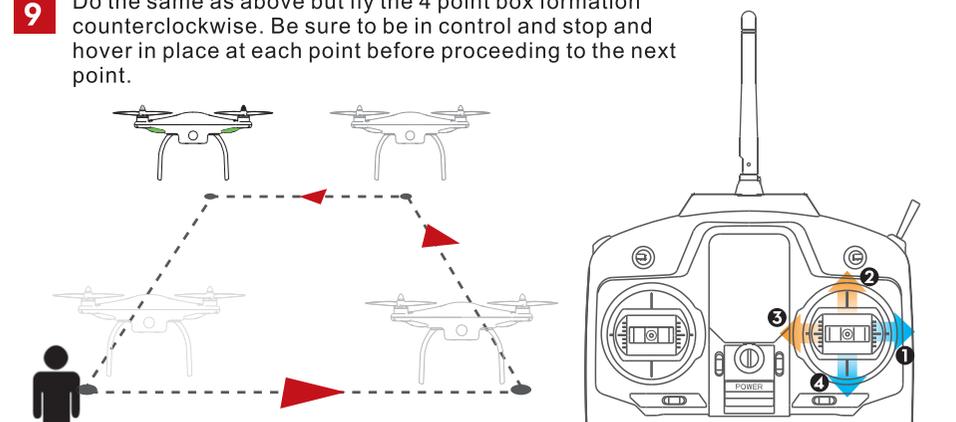
- 7** Fly left 10ft away from the takeoff point, then fly right 10ft from the takeoff point and keep the tail end of the quadcopter faces you.



- 8** While keeping the tail end of the quadcopter faces you, fly a 4 point square box formation going clockwise. Be sure to be in control and stop and hover in place at each point before proceeding to the next point.

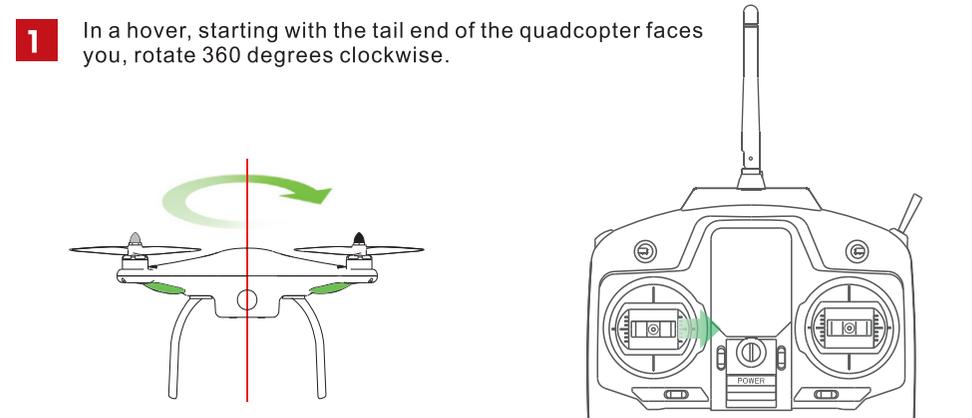


- 9** Do the same as above but fly the 4 point box formation counterclockwise. Be sure to be in control and stop and hover in place at each point before proceeding to the next point.

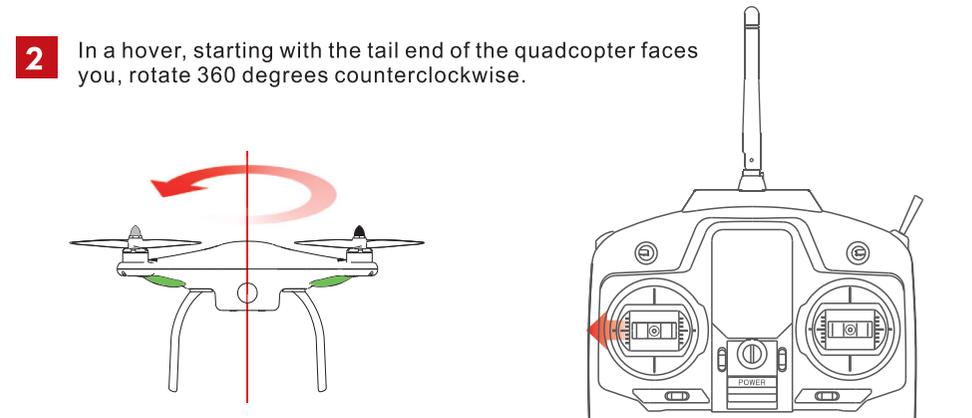


Skilled Flight Maneuvers

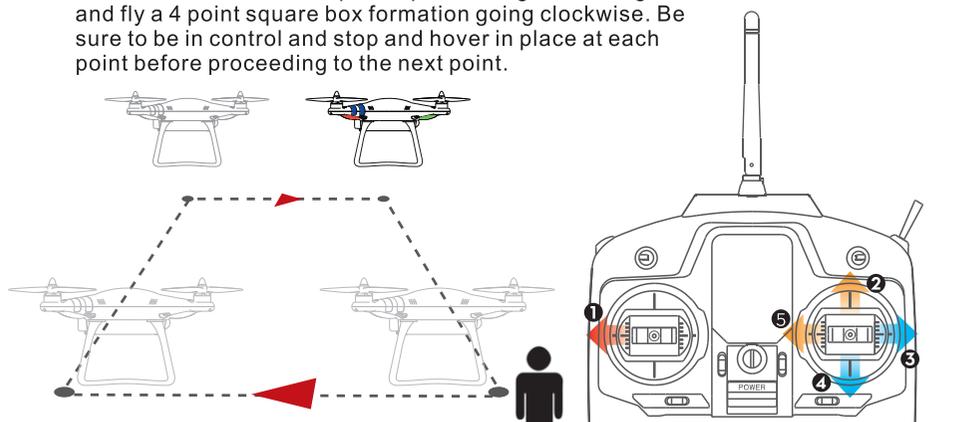
- 1** In a hover, starting with the tail end of the quadcopter faces you, rotate 360 degrees clockwise.



- 2** In a hover, starting with the tail end of the quadcopter faces you, rotate 360 degrees counterclockwise.

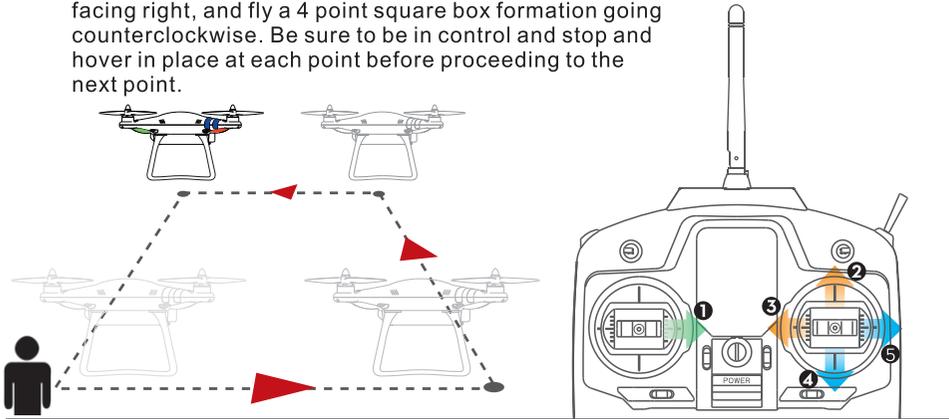


- 3** Starting with the tail end of the quadcopter faces you, go into a hover. Then rotate the quadcopter 90 degrees facing left, and fly a 4 point square box formation going clockwise. Be sure to be in control and stop and hover in place at each point before proceeding to the next point.

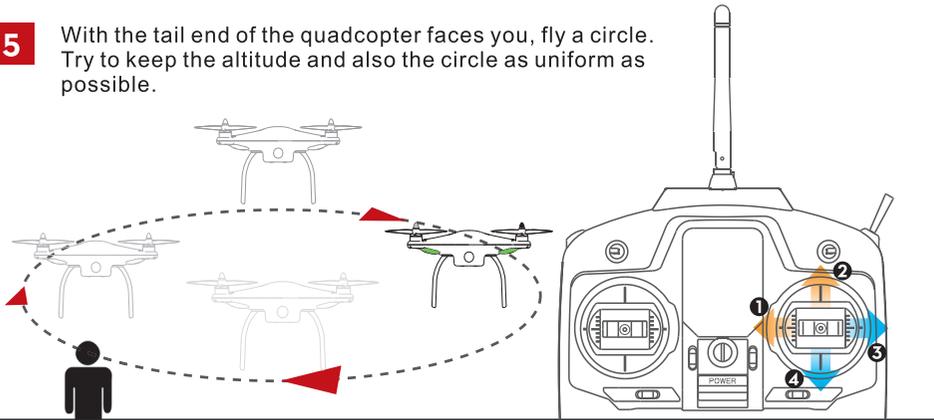


Skilled Flight Maneuvers

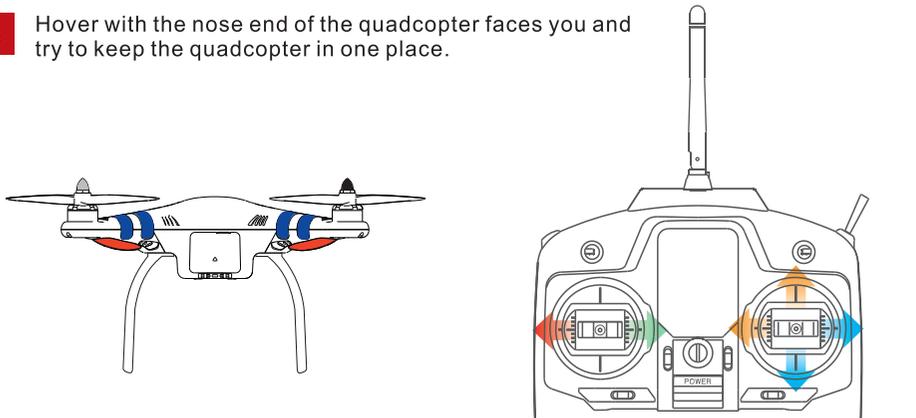
- 4** Starting with the tail end of the quadcopter faces you, go into a hover. Then rotate the quadcopter 90 degrees facing right, and fly a 4 point square box formation going counterclockwise. Be sure to be in control and stop and hover in place at each point before proceeding to the next point.



- 5** With the tail end of the quadcopter faces you, fly a circle. Try to keep the altitude and also the circle as uniform as possible.

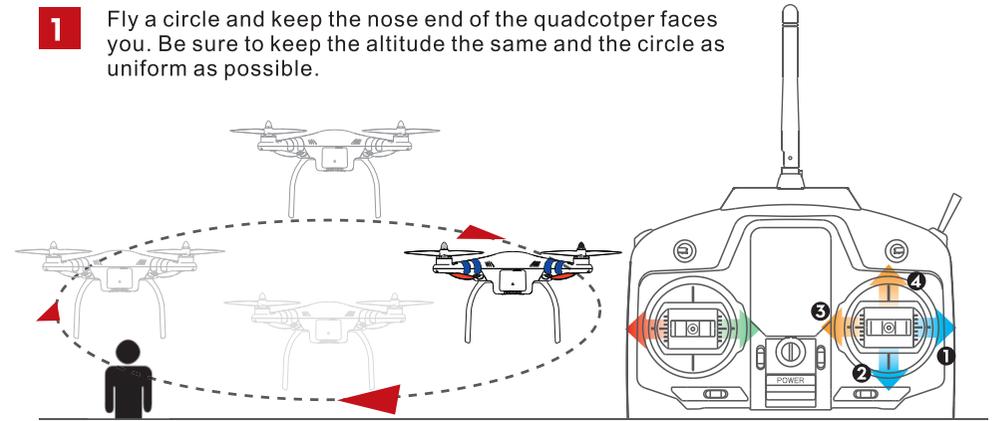


- 6** Hover with the nose end of the quadcopter faces you and try to keep the quadcopter in one place.

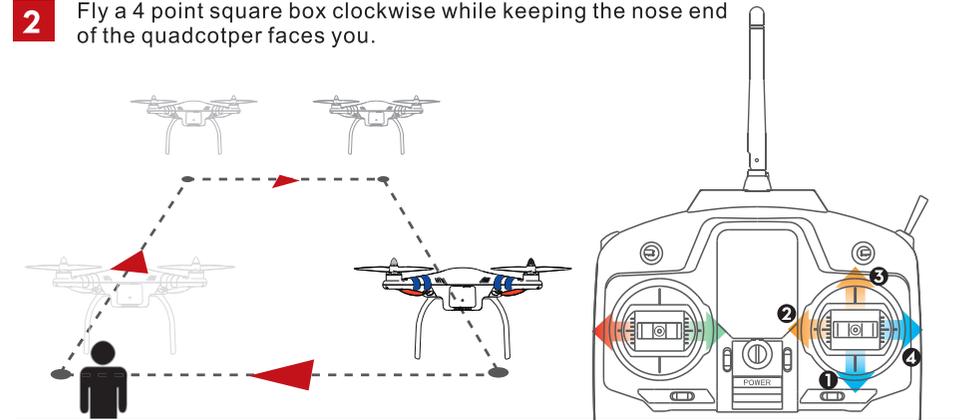


Advanced Flight Maneuvers

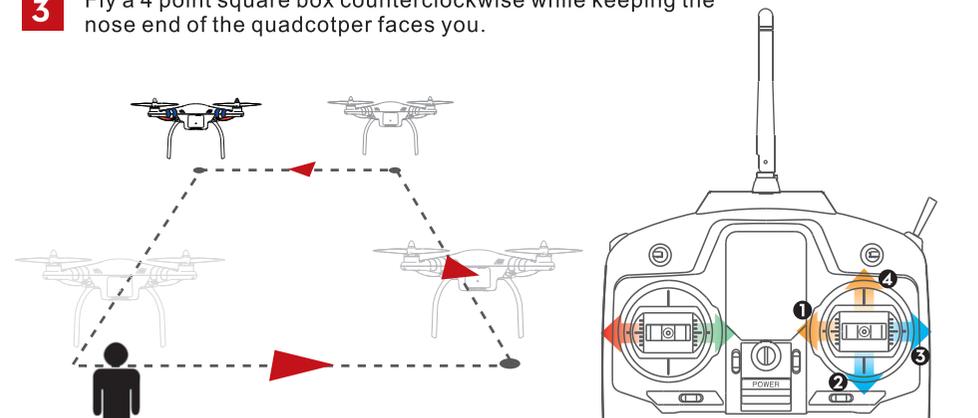
- 1** Fly a circle and keep the nose end of the quadcopter faces you. Be sure to keep the altitude the same and the circle as uniform as possible.



- 2** Fly a 4 point square box clockwise while keeping the nose end of the quadcopter faces you.

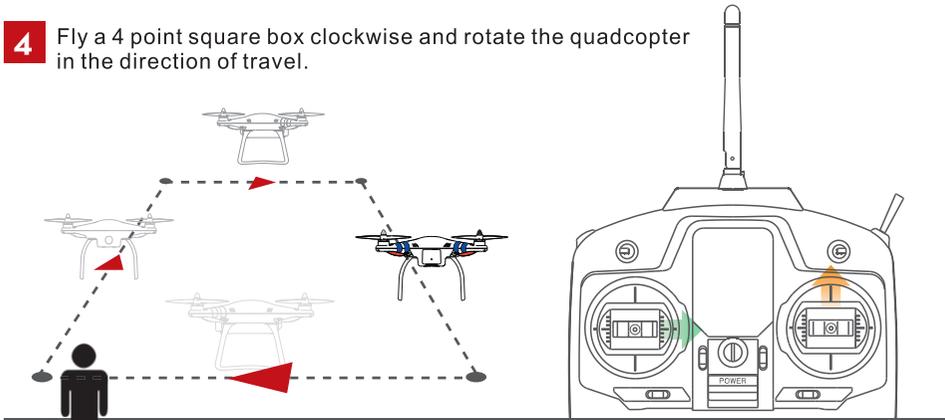


- 3** Fly a 4 point square box counterclockwise while keeping the nose end of the quadcopter faces you.

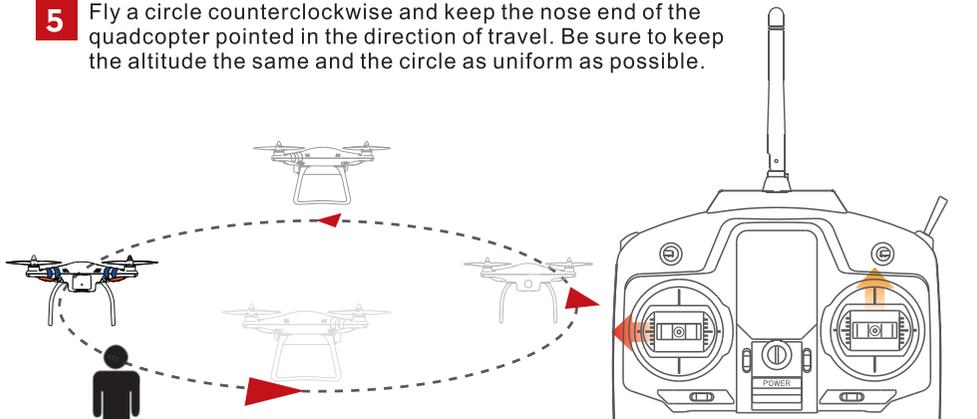


Advanced Flight Maneuvers

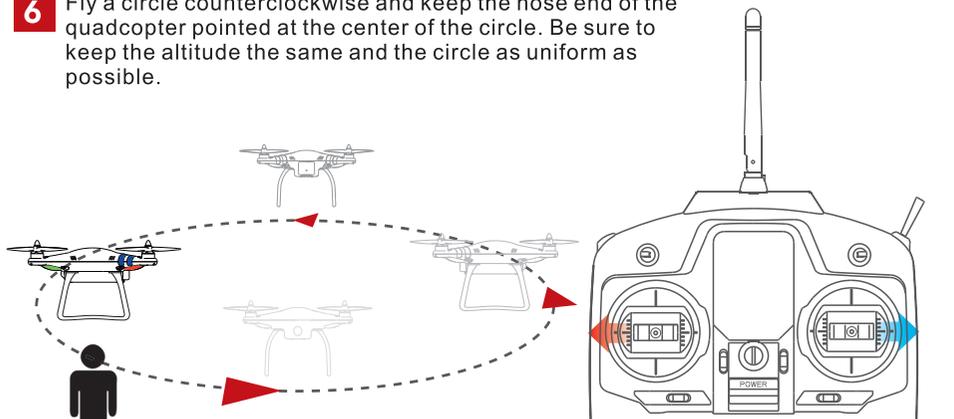
- 4** Fly a 4 point square box clockwise and rotate the quadcopter in the direction of travel.



- 5** Fly a circle counterclockwise and keep the nose end of the quadcopter pointed in the direction of travel. Be sure to keep the altitude the same and the circle as uniform as possible.

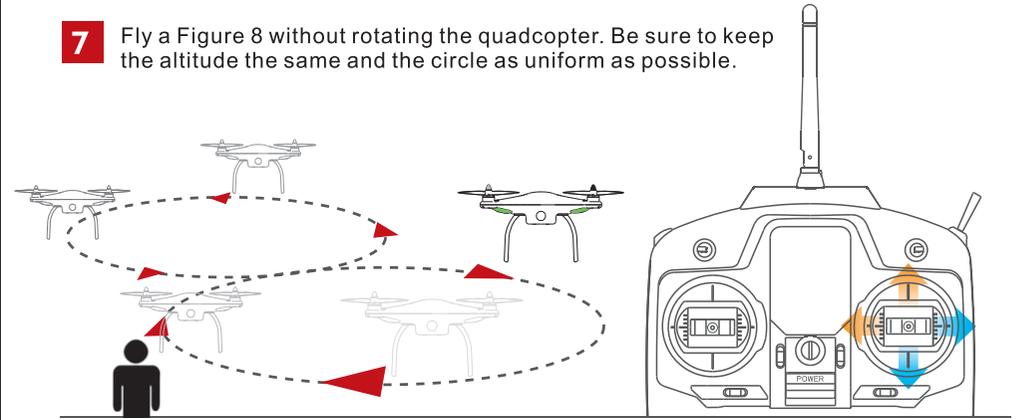


- 6** Fly a circle counterclockwise and keep the nose end of the quadcopter pointed at the center of the circle. Be sure to keep the altitude the same and the circle as uniform as possible.

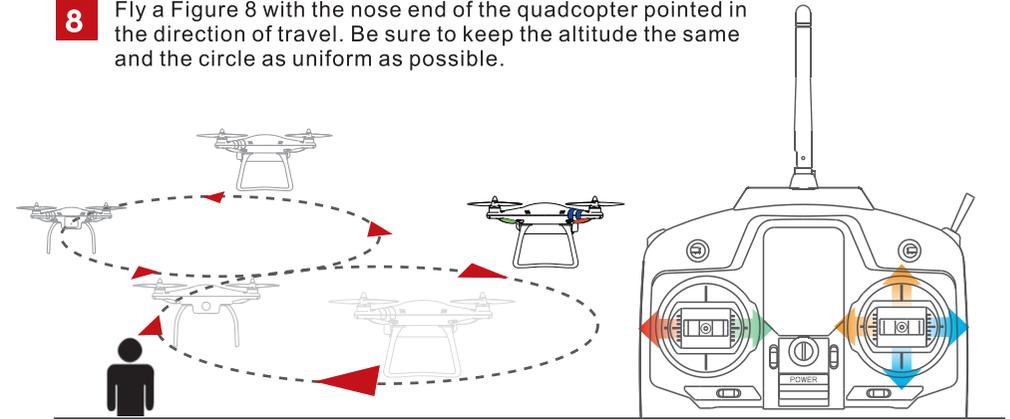


Advanced Flight Maneuvers

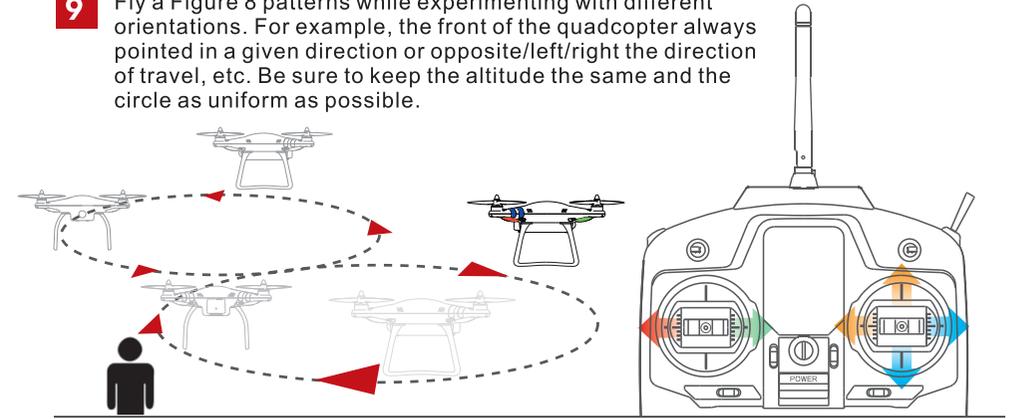
- 7** Fly a Figure 8 without rotating the quadcopter. Be sure to keep the altitude the same and the circle as uniform as possible.



- 8** Fly a Figure 8 with the nose end of the quadcopter pointed in the direction of travel. Be sure to keep the altitude the same and the circle as uniform as possible.



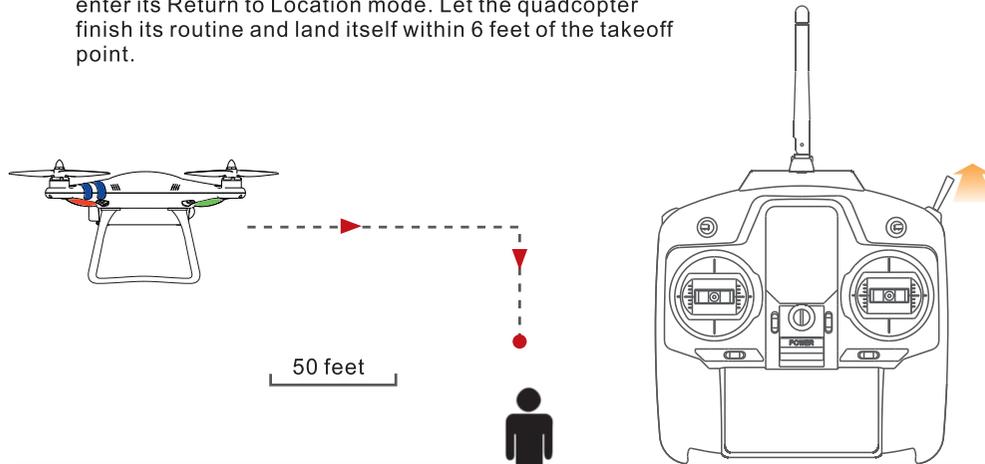
- 9** Fly a Figure 8 patterns while experimenting with different orientations. For example, the front of the quadcopter always pointed in a given direction or opposite/left/right the direction of travel, etc. Be sure to keep the altitude the same and the circle as uniform as possible.



Emergency Situations

1 Return to Location Mode

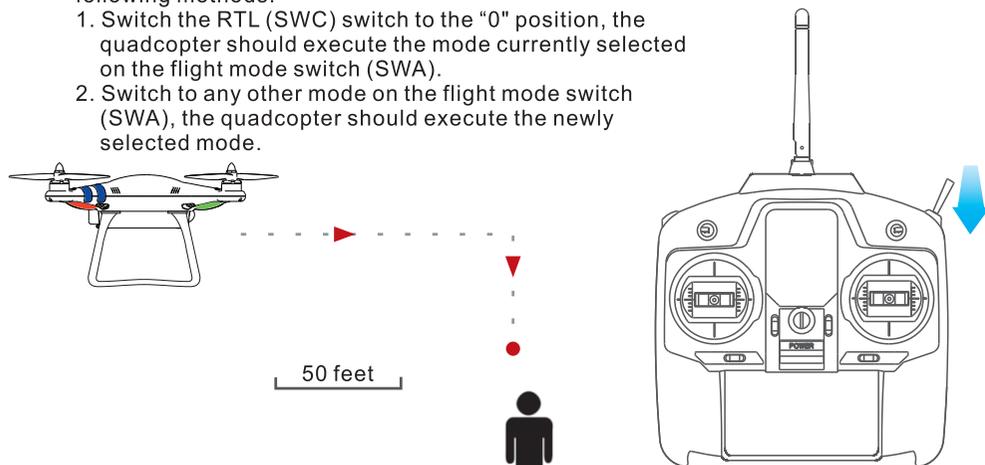
Be sure you are in a large open area. Before you take off, make sure you have a good GPS lock by ensuring the green status light becomes solid. Fly the quadcopter at least 50ft away from the takeoff point. Toggle the RTL (SWC) switch to the "1" position, the quadcopter should enter its Return to Location mode. Let the quadcopter finish its routine and land itself within 6 feet of the takeoff point.



2 Intercepting the Return to Location mode

Be sure you are in a large open area. Before you take off, make sure you have a good GPS lock by ensuring the green status light becomes solid. Fly the quadcopter 50ft away from your takeoff point. Toggle the RTL (SWC) switch to the "1" position, the quadcopter should enter its Return to Location mode. When the quadcopter is returning home, you can intercept the RTL mode with the following methods:

1. Switch the RTL (SWC) switch to the "0" position, the quadcopter should execute the mode currently selected on the flight mode switch (SWA).
2. Switch to any other mode on the flight mode switch (SWA), the quadcopter should execute the newly selected mode.

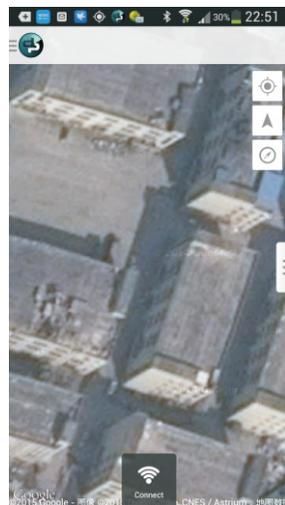


Datalink and ground station APP support (optional):

The quadcopter supports the Droidplanner V2 ground station APP. Install this APP from GooglePlay store on your android device (APP requires Android 4.0 and Google service framework 4.1.2). The datalink transmitter and receiver modules are sold separately.

Install the datalink modules.

1. Install and connect the datalink transmitter module on the quadcopter. Connect the battery on the quadcopter.
2. Connect the datalink receiver module to the android device.
3. Open the Droidplanner APP.
4. Press the "Connect" function button on the bottom of the screen to establish datalink connection between the APP and the quadcopter.



Using the Droidplanner APP

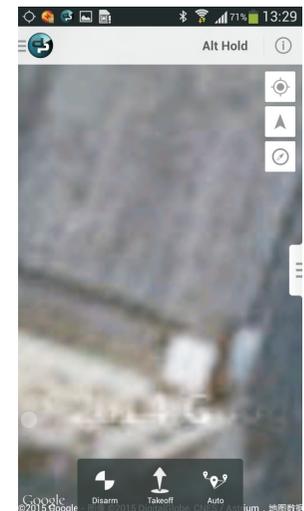
Arming the quadcopter:

For safety purpose, you need to arm the quadcopter with the radio transmitter before using the arming function on the ground station APP (see how to arm the quadcopter on user manual). GPS lock is required when using the ground station APP to arm the quadcopter. Press the "Arm" function button on the bottom of the screen to arm the quadcopter (see safety instruction for arming the quadcopter on user manual).



Take off automatically:

After the quadcopter is armed, you should see the "Takeoff" function button on the bottom of the screen. Press the "Takeoff" function button, the quadcopter should take off automatically and level at around 30 feet from the ground. (keep a safe distance from the quadcopter before taking off, see safety instruction on user manual).



Guided position control:

Press a new location point on the map screen for 3 seconds, the quadcopter should fly to that location automatically. Do not shrink the map too much, or you might select a location point too far away, and the quadcopter does not have enough battery power to return safely. The map screen should show the flight patch of the quadcopter.

After taking off, the bottom of the screen should show some new function buttons.

Home (Return To Location):

Press the "Home" function button to execute the RTL mode (Return To Location).

Landing automatically:

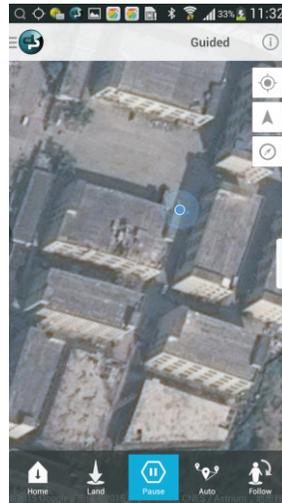
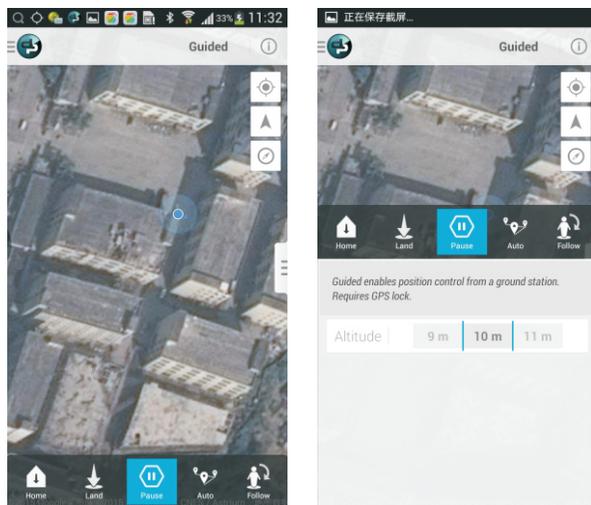
Press the "Land" function button to land the quadcopter at the current location.

Follow me function:

When pilot moves to a new location with the device that runs the ground station APP, the quadcopter will follow the move automatically. The device that runs the ground station APP must have GPS capability.

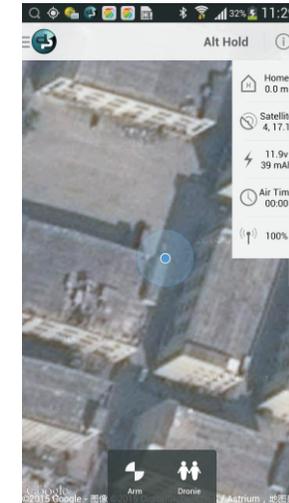
Adjusting the flight altitude of the quadcopter:

Press and drag the "Pause" function button upward to show the altitude adjustment screen. You can adjust the flight altitude of the quadcopter by scrolling the number ruler left or right.



Checking the flight status of the quadcopter:

Press the "Information" button on the upper right screen to view the flight status of the quadcopter.



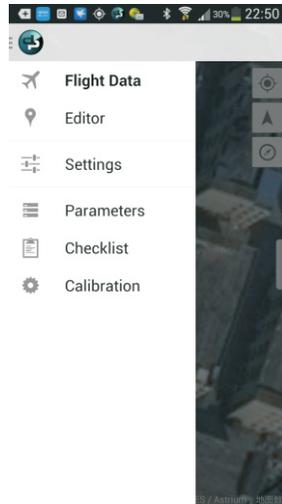
Changing the flight command mode:

Only the following flight modes are supported on this quadcopter:

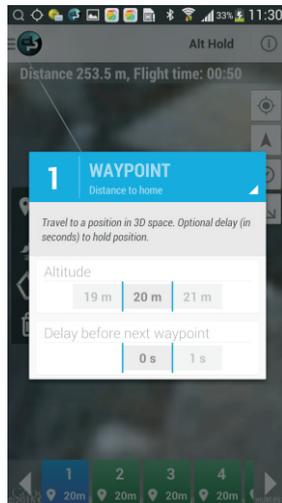
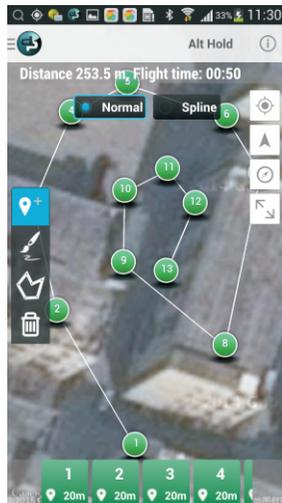
- ALT HOLD** : Quadcopter maintains the altitude automatically.
- AUTO** : Quadcopter executes the flight plan uploaded to the quadcopter from the ground station APP.
- Guided** : Quadcopter flies to a location set on the map screen on the ground station APP.
- Lotier (GPS Hold)** : Quadcopter maintains altitude, location, and heading automatically.
- RTL (Return To Location)** : Quadcopter returns to the home location automatically.
- LAND:** : Quadcopter lands at the current location automatically.

Creating a flight plan:

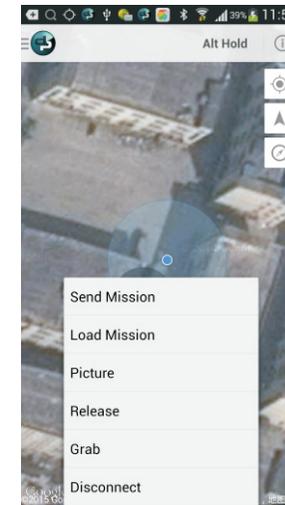
Press the “☰” button on the upper left screen, select “Editor” on the dropdown menu.



Press and draw a flight path on the screen. The APP should create a list of waypoints on the path automatically. Select and press the green button on the bottom of the screen to adjust the stopping duration and altitude for each waypoint. Pilot should design the flight plan within the range limit of the radio transmitter. The quadcopter should execute the RTL model (Return to Location) when it reaches the range limit of the radio transmitter automatically.



Upload waypoints to the quadcopter by selecting the "Send Mission" menu function.



Press the “☰” button on the upper left screen and select “Flight Data” on the dropdown menu. Press the "Auto" function button on the bottom of the screen. The quadcopter should take off, execute the flight plan, and land automatically.

