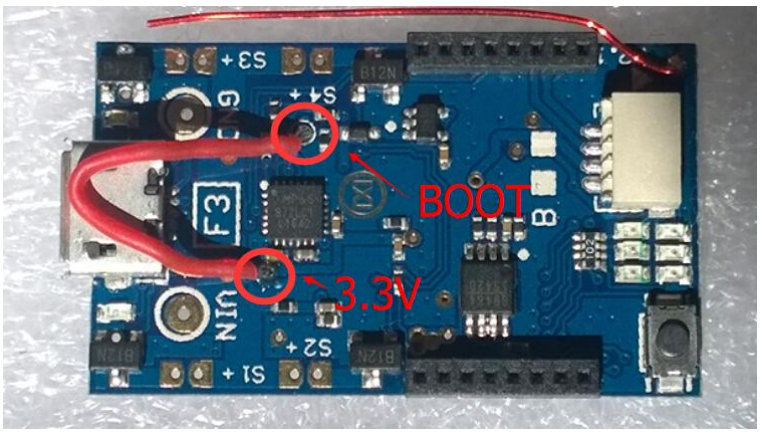
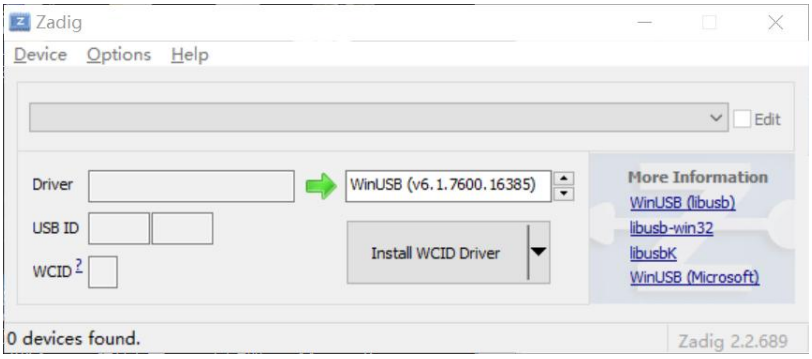
Scisky F3 firmware flashing Guide

Step 1: Download Zadig software from http://zadig.akeo.ie (please ignor it if it was already downloaded)

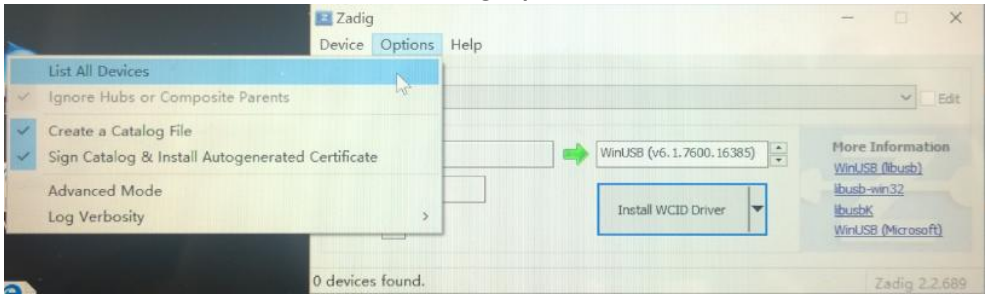
Step 2: short connect BOOT and 3.3V ports on the flight control board, please check the following picture by reference:



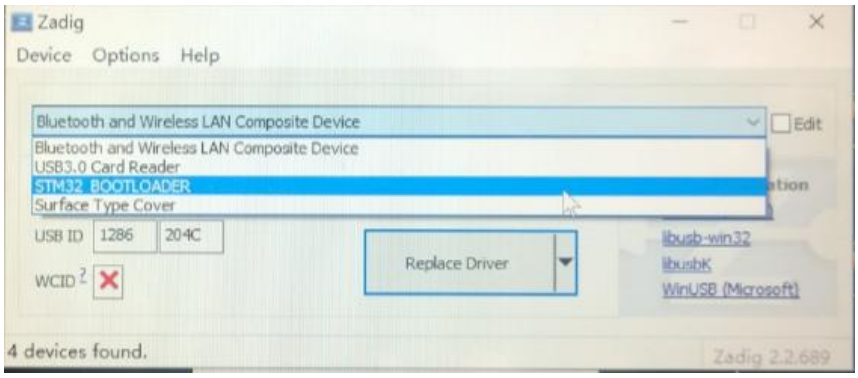
Step 3: connect Scisky F3 flight control board to computer through USB cable, open Zadig software:



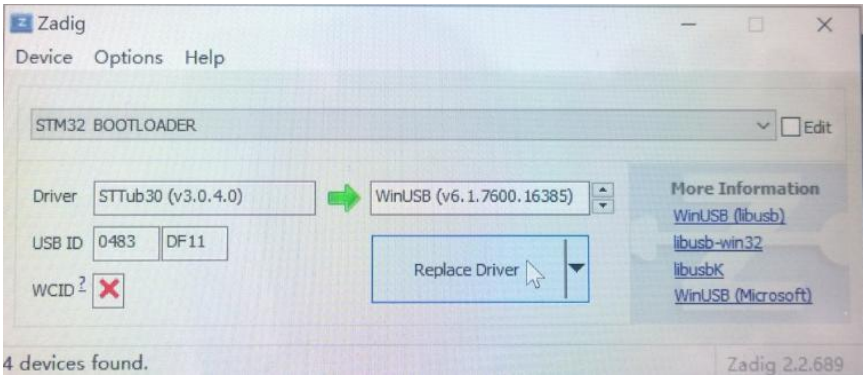
Choose “List ALL Devices” among options:



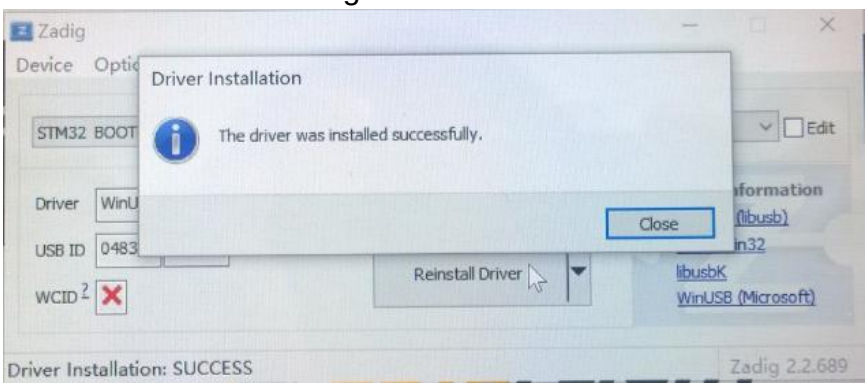
Choose STM32 BOOTLOADER



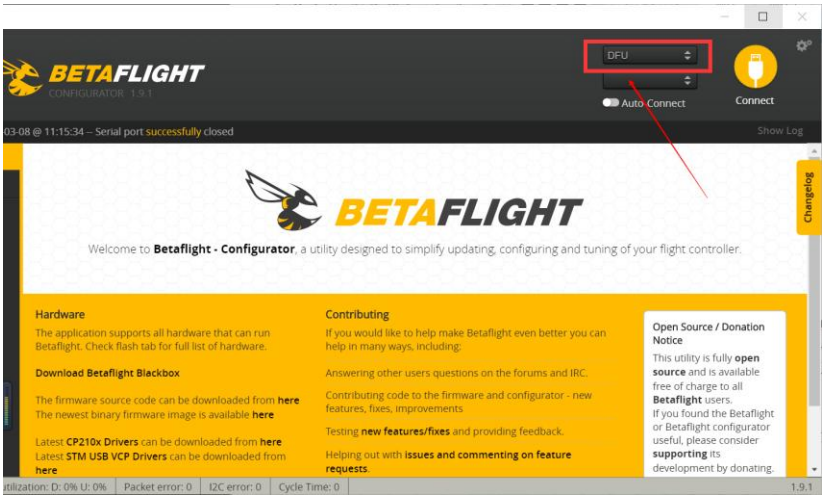
Click “Replace Driver” for installing driver:



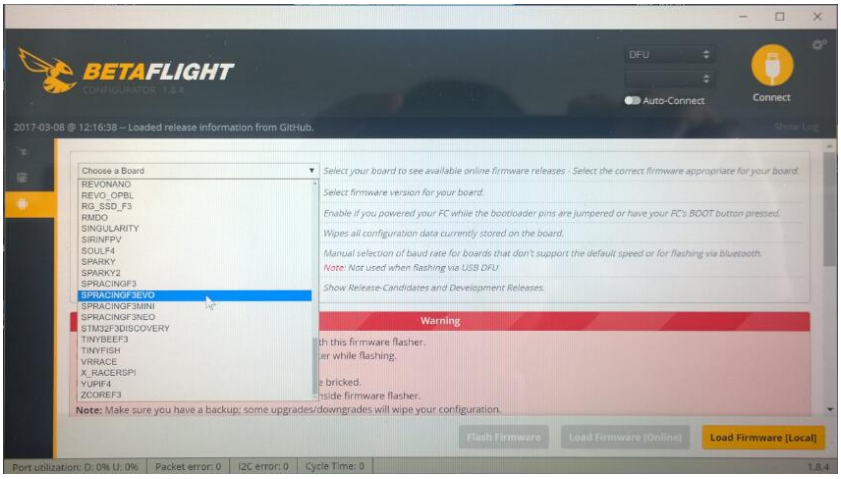
Click “Close”and shut off Zadig software after the installation:

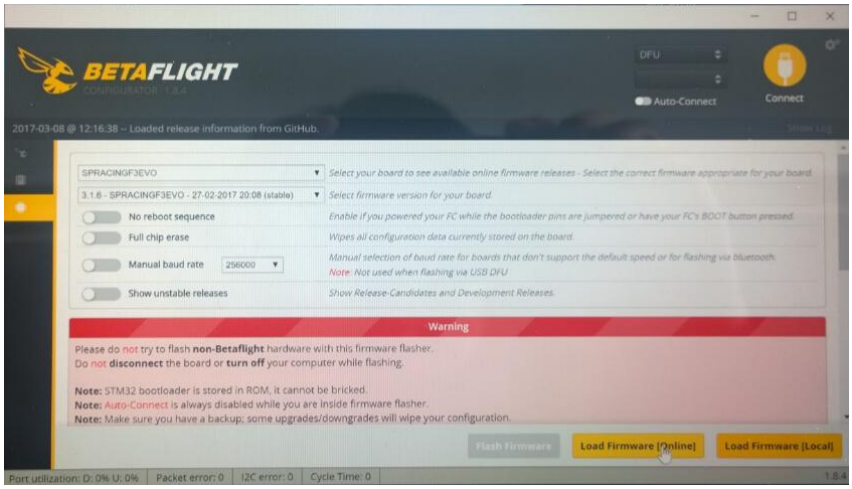


Step 4: Disconnect Scisky F3 brushed FC with computer and then connect them again, open BETAFLIGHT or CLEANFLIGHT software, its COM port will be displayed as DFU:



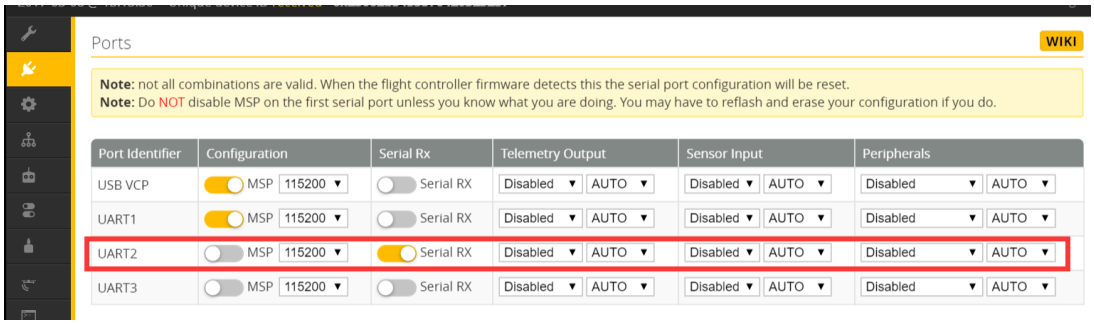
Turn to firmware upgrading page, select SPRACINGF3EVO and firmware, and load the firmware.

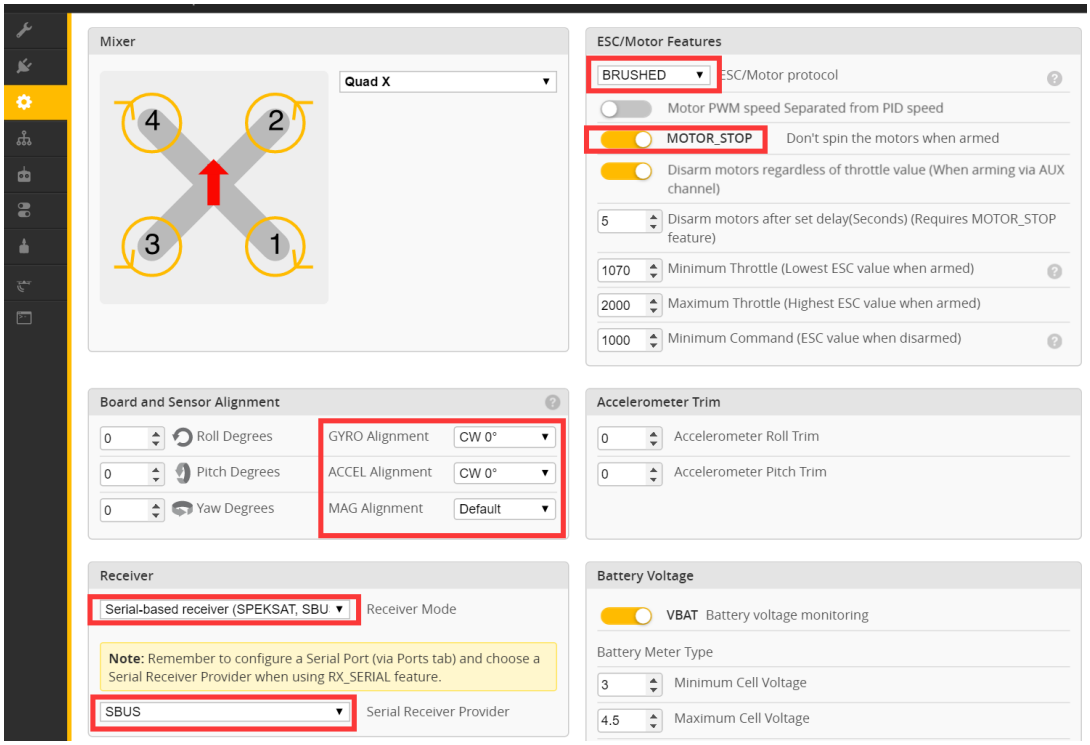


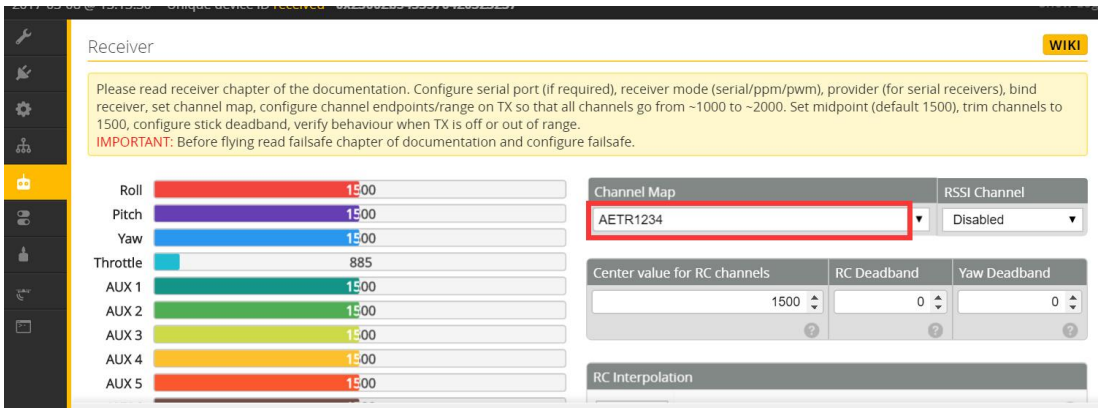


Disconnect Scisky F3 FC with computer after finishing firmware upgrading, and then disconnect BOOT and 3.3V, connect Scisky F3 FC with computer again, enter set up page of BETAFLIGHT or CleanFlight GUI and change the parameters for receiver, ESC or sensor.

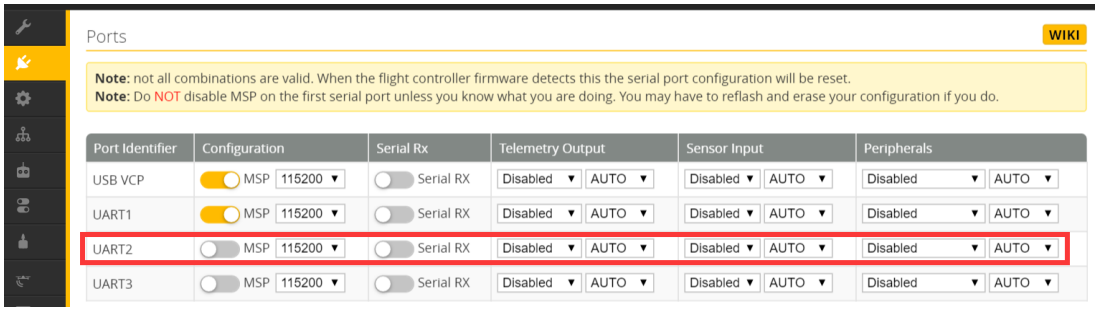
Set up for Scisky F3-A/B(DSMX/2, SFHSS, FRSKY outputs SBUS signal) as the following:

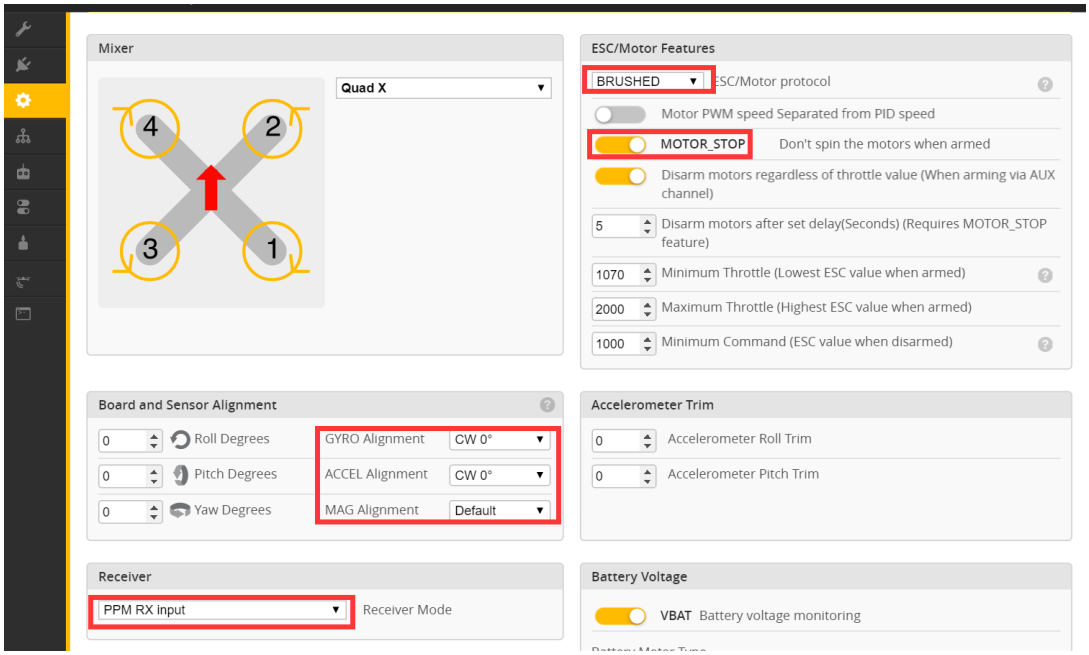


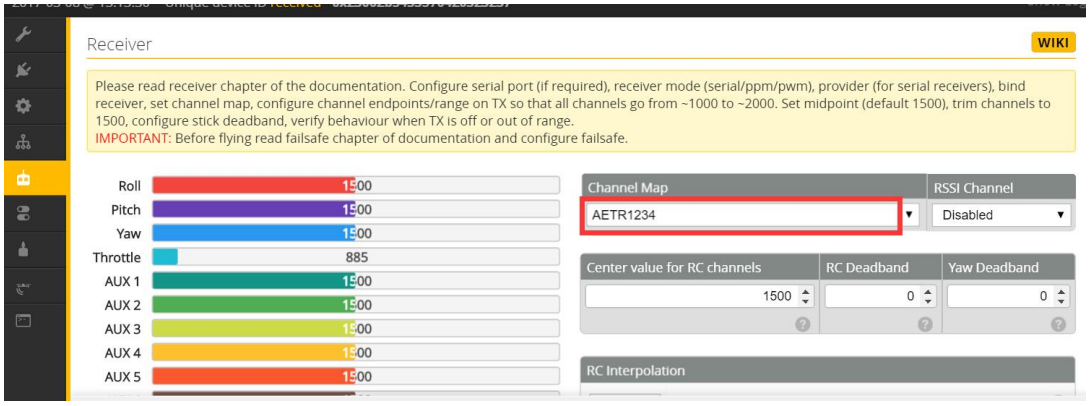




Setting up for Scisky F3-C receiver(FlySky, Hubsan outputs PPM signal) is as the following:




Mixer
Quad X
4
2
3
1
ESC/Motor Features
BRUSHED
ESC/Motor protocol
Motor PWM speed Separated from PID speed
MOTOR_STOP
Don't spin the motors when armed
Disarm motors regardless of throttle value (When arming via AUX channel)
5
Disarm motors after set delay(Seconds) (Requires MOTOR_STOP feature)
1070
Minimum Throttle (Lowest ESC value when armed)
2000
Maximum Throttle (Highest ESC value when armed)
1000
Minimum Command (ESC value when disarmed)
Board and Sensor Alignment
0
Roll Degrees
0
Pitch Degrees
0
Yaw Degrees
GYRO Alignment
CW 0°
ACCEL Alignment
CW 0°
MAG Alignment
Default
Accelerometer Trim
0
Accelerometer Roll Trim
0
Accelerometer Pitch Trim
Receiver
PPM RX input
Receiver Mode
Battery Voltage
VBAT
Battery voltage monitoring


Receiver
WIKI
Please read receiver chapter of the documentation. Configure serial port (if required), receiver mode (serial/ppm/pwm), provider (for serial receivers), bind receiver, set channel map, configure channel endpoints/range on TX so that all channels go from ~1000 to ~2000. Set midpoint (default 1500), trim channels to 1500, configure stick deadband, verify behaviour when TX is off or out of range.
IMPORTANT: Before flying read failsafe chapter of documentation and configure failsafe.
Roll
Pitch
Yaw
Throttle
885
AUX 1
AUX 2
AUX 3
AUX 4
AUX 5
Channel Map
AETR1234
RSSI Channel
Disabled
Center value for RC channels
1500
RC Deadband
0
Yaw Deadband
0
RC Interpolation