## A-B Point Take-off & Landing Route Planning

First add a waypoint before the point where you need to land, with the waypoint set to DO\_DIGCAM\_CONFIGURE.



		Command		Mode	Shutte Speed	Apertu	ISO	ExposureMo	CommandID		Frame	Delete		Grad %	Angle	Dist	AZ
	1	WAYPOINT	×	0	0	0	0	39.0253073	117.133	50	Rela 🗡	X	ΦÐ	37.7	20. 7	1	37
	2	WAYPOINT	×	0	0	0	0	39.0257273	117.135	50	Rela 🗠	X	44	0.0	0.0	2	77
	3	WAYPOINT	×	0	0	0	0	39.0254147	117.137	50	Rela 🗠	X	44	0.0	0.0	2	99
Ð	4	DO_DIGICAM_CONFIGURE	~	98	10	15	30	34	0	1	Rela 🗠	X	40	0.0	0.0	2	184

As shown in Waypoint 4, set to DO\_DIGCAM\_CONFIGURE in the command menu.

From left to right, fill in the following order.

98: A-B point take-off and landing orders must be 98

10: Descend to 10m altitude to the ground (set to 0: land on the ground and disarm)

15: Wait 15S and then arm for take-off, or hover for 15S if not landing on the ground. (Set to 0: manually arm the drone with the button to take off)

30: Take off to 30m altitude for multirotor-vtol mode conversion.

34: Drop and release device

0: empty

1: Drop-device release ( the value can be set to 0, but feasibility needs to be verified by yourself) The landing point command is set to VTOL\_

	Command						Lat	Long	Alt	Frame	Delete		Grad %	Angle	Dist	ΑZ
1	WAYPOINT	×	0	0	0	0	39.0253073	117. 133	50	Rela 🗠	X	ΦÐ	37. 7	20. 7	1	37
2	WAYPOINT	v	0	0	0	0	39.0257273	117.135	50	Rela 🗸	X	40	0.0	0.0	2	77
3	WAYPOINT	×	0	0	0	0	39.0254147	117. 137	50	Rela 🗠	X	40	0.0	0.0	2	99
4	DO_DIGICAM_CONFIGURE	×	98	10	15	30	34	0	1	Rela 🗠	X	ΦÐ	0.0	0.0	2	184
<b>a</b> 5	VTOL_LAND	$\sim$	15	0	0	0	39.0227426	117.133	5	Rela 🗸	X	ΦÐ	0.0	0.0	4	232

	Command			Acc radius	Pass by		Lat	Long	Alt	Frame	Delete		Grad %	Angle	Dist	AZ
1	WAYPOINT	$\sim$	0	0	0	0	39.0253073	117.133	50	Rela 🗠	X	44	37.7	20. 7	1	37
2	WAYPOINT	$\sim$	0	0	0	0	39.0257273	117.135	50	Rela 🗠	X	44	0.0	0.0	2	77
3	WAYPOINT	$\sim$	0	0	0	0	39.0254147	117.137	50	Rela 🗡	X	44	0.0	0.0	2	99
4	DO_DIGICAM_CONFIGURE	$\sim$	98	10	15	30	34	0	1	Rela 🗠	X	ΦΦ	0.0	0.0	2	184
5	VTOL_LAND	$\sim$	15	0	0	0	39.0227426	117.133	5	Rela 🗠	X	ΦÐ	-9.4	-5.4	4	232
6	WAYPOINT	$\sim$	0	0	0	0	39.0223192	117.128	50	Rela 🗠	X	40	10.6	6.1	4	264
7	WAYPOINT	~	0	0	0	0	39.0203527	117.128	50	Rela 🗠	X	44	0.0	0.0	2	189
8	WAYPOINT	~	0	0	0	0	39.0208998	117.137	50	Rela 🗠	X	ΦΦ	0.0	0.0	8	86
9	WAYPOINT	~	0	0	0	0	39.0190177	117.138	50	Rela 🗠	X	ΦÐ	0.0	0.0	2	172
10	WAYPOINT	$\sim$	0	0	0	0	39.0187539	117.128	50	Rela 🗠	X	ΦΦ	0.0	0.0	8	268
11	WAYPOINT	$\sim$	0	0	0	0	39.0172210	117.128	50	Rela 🗠	X	ΦΦ	0.0	0.0	1	182
12	WAYPOINT	~	0	0		0	39.0178002	117.137	50	Rela 🗠	X	<u> </u>	0.0	0.0	7	85

Set in order from left to right:

15: Begin to slow down when descend to an altitude of 15 meters.

5: Height difference from home point (can be set without the installation of height-fixed radar)

Leave the rest of the space unchanged.

Note: After A-B point take-off and landing, the regular waypoint flight is still available. (If the route is too high to land directly, please add way points for descending before entering the A-B point flight, to avoid insufficient power due to keeping too long in VTOL status. Also can add way points for climbing before entering regular route flight.)



As shown in the picture the drone can automatically return to launch after the flight is completed without being affected.