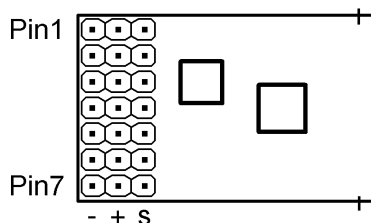


DT 2.4GHz RECEIVER INSTRUCTIONS

Rx100-SA (v2.6)



The receiver will work with DSM2 transmitters (surface and air).
Protect from shock, vibration and moisture
Operating temperatures are 0 to 70°C.

A battery may be connected with correct orientation to any +/- pin (3.2-10v).
Bind twice, once to create the link and again to save correct failsafe positions.
If throttle failsafe is set correctly, the Tx/Rx may be switched on/off in any order.

LED:

Led ON = perfect reception (real-time indicator).

Led OFF = not perfect (useful for range tests/interference indicator).

1 flash = scanning (~2sec between flashes; wrong model if never stops).

2 flash = brownout (receiver voltage went too low; check battery/servo load).

3 flash = timeouts (accumulation of short signal failures; should not see often).

4 flash = failsafe (signal lost for >1s eg: Tx switched off before Rx).

5 flash = watchdog (program recovery mechanism; should never happen).

FAILSAFE:

Servos go to failsafe positions on startup (except Throttle to avoid confusing ESCs)

- Sequential PPM and Serial signals are not generated until a signal is acquired.

Servos 'hold' on short signal losses (<1s) (including Throttle & SeqPPM).

Servos go to failsafe positions after 1s sustained signal loss (incl. Thr & SeqPPM).

BINDING (and memorising servo failsafe positions)

1. Put bind plug on bind pins (signal pins 1 & 2) and switch Rx on (=Bind mode). Led will flash rapidly. Do not remove bind plug until binding is complete.
2. Hold Tx bind switch and switch Tx on. Led will flash twice a second for several seconds.
3. Bind is complete when Led stays On. Stick positions are memorised for failsafe immediately before the Led comes on solid.
4. If Led does not come on within 10sec or continues flashing every 2sec (=scanning) the bind has failed. Switch Tx and Rx off, move them closer or further apart and retry. Binding is most reliable when no other RC 2.4 Tx's are on.

DT 2.4GHZ RECEIVER INSTRUCTIONS (cont)

CONFIGURABLE OPTIONS:

1. Servo outputs on all pins (default)
2. Sequential PPM output on Pin7

1.1 SERVO OUTPUTS WITH 'AIR' TRANSMITTERS

Pin1 Throttle, Pin2 Aileron, Pin3 Elevator, Pin4 Rudder, Pin5 Gear,
Pin6 Aux1, Pin7 Aux2.

The receiver is intended to be used at 22ms frame length.

1.2 SERVO OUTPUTS WITH 'SURFACE' TRANSMITTERS (DX3)

Pin1 & 4 Steering, Pin2 & 5 Throttle, Pin3 & 6 Aux.

The receiver is intended to be used at 16.5ms frame length.

2. SEQUENTIAL PPM:

This option strings 7 channels together into a consolidated 'summed' PPM output on one pin. The output is normally High (logic 1) with 300us Low trigger pulses. Either the falling or rising edge may be used for triggering. The channel order is 1,2,3,4,5,6,7 (Throttle, Aileron, Elevator, Rudder, Gear, Aux1, Aux2).

PROGRAMMING APPROACH:

Options are selected with the bind plug using 'yes/no' selections.

Bind pin on pins 1&2='no', pins 2&3='yes' (signal pins).

The bind pin needs to be placed on the pins and removed again to take effect.

The led flashes the option currently presented (1 or 2 flashes 1sec apart).

PROGRAMMING PROCEDURE:

1. Place bind plug on signal pins 1&2 and switch Rx on; Rx will enter bind mode; led will flash rapidly
2. Remove bind plug to enter Programming mode; Led will repeat a single-flash for the first configurable option (servo outputs).
3. To accept an option place bind plug on pins 2&3 and remove again. No further changes can be made until the Rx is switched off.
4. To move on to next option place bind plug on pins 1&2 and remove again. Led flashes will increase by one.
5. Switch Rx off at any time without placing bind plug on pins 2&3 to exit without saving changes.