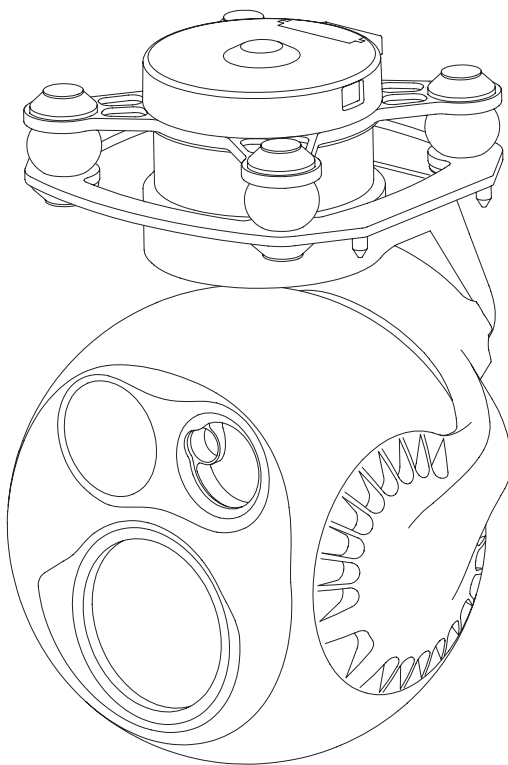


# D-90<sub>DE</sub>

## User Manual



# Using this Manual – Legend



Important



Tips



Explanation

# Revision History

| Date       | Document Version |
|------------|------------------|
| 2024.03.04 | V1.0             |

| Date       | Document Version |
|------------|------------------|
| 2024.10.16 | V1.1             |

| Date       | Document Version |
|------------|------------------|
| 2025.02.08 | V1.2             |

## Caution

1. When not in use, store the D-90 in the package box. The recommended storage environment is a relative humidity less than 40% at a temperature of  $20\pm5^{\circ}\text{C}$ . If the lenses fog up. The water vapor will usually dissipate after turning on the device for a while.
2. Do not place the product under direct sunlight, in areas with poor ventilation, or near a heat source such as a heater.
3. Do not frequently power on/off the product. After it is turned off, wait at least 30 seconds before turning back on, otherwise the product life will be affected.
4. Make sure the pod port and pod surface are free from any liquid before installation.
5. Make sure the pod is securely installed onto the aircraft, the microSD card slot cover is clean and firmly in place.
6. Make sure the pod surface is dry before opening the microSD card slot cover.
7. Do not plug or unplug the microSD card during use.
8. Do not touch the surface of the camera lenses and keep it away from hard objects. As doing so may lead to blurred images and affect the imaging quality.
9. Clean the surface of the camera lenses with a soft, dry, clean cloth. Do not use alkaline detergents.
10. When not receiving valid carrier INS data, the yaw shaft of the pod will drift about 15 degrees per hour because of the earth rotation. To make sure the pod attitude corrects, it is necessary to transmit valid carrier INS data, usually the GNSS should be positioning.
11. When its damping platform tilted over  $45^{\circ}$ , the pod will trigger protection mode and return to its neutral position. (except in FPV mode)

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# Introduction

## Synopsis

The D-90DE equips with a high accuracy 3-axis nonorthogonal gombal, a wide-angle camera and a 30x hybrid zoom camera. User can quickly switch to a highly magnified zoom camera view after recognizing a target in a wide camera view. Thanks to the laser range finder, the D-90DE can provide the location of a target and the distance to it that improves working efficiency.

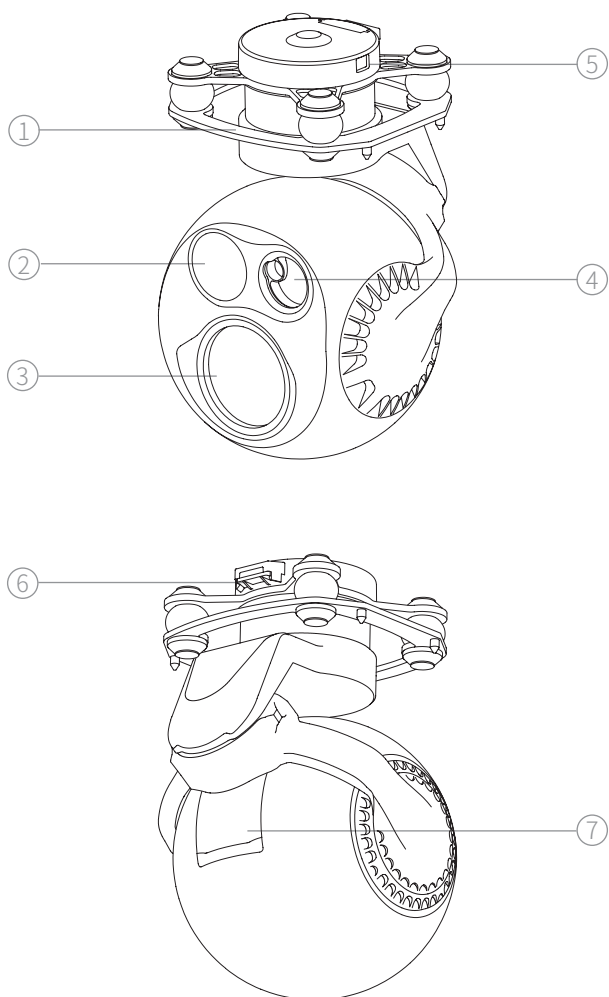
The D-90DE have AI multi-object detection and tracking function. The gimble camera can intelligently identify the persons and vehicles in the image, and constantly track one of them.

The D-90DE can be mounted tool-lessly onto multiple carriers, whether downward or upward. With the GCU and the Dragonfly software, user can watch the image from the camera and control the pod real-timely on a computer.

## Characteristics

- Features AI multi-object detection and tracking, which can constantly track one of the persons and vehicles intelligently identified in the image.
- Combination of wide-angle camera and 30x hybrid zoom camera, which can quickly switch between overall and detailed view.
- Laser range finder provides the location of a target and the distance to it.
- Low-profile spherical shape and 3-axis nonorthogonal mechanical stabilized structure, minimize the gyration radius and the wind resistance of the pod. The D-90DE is able to spin continually around its yaw axis.
- With the GCU, the D-90DE supports network, UART and S.BUS control. The GCU supports both private protocol and MAVLink protocol.
- Thanks to the Dual-IMU complementary algorithms with IMU temperature control and carrier AHRS fusion, the D-90DE provides a stabilization accuracy at  $\pm 0.01^\circ$ .
- Can be mounted onto multiple carriers, whether downward or upward.
- With the GCU and the Dragonfly software, user can watch the image and control the pod without protocol ducking.
- Screen supports overlaying OSD information such as latitude, longitude and altitude. Image supports shooting point coordinate EXIF save. Video stream supports SEI stacking.
- 14~53 VDC wide voltage input.

## Overview



1. Damping Platform

3. Zoom Camera

5. Upgrade Port

7. MicroSD Card Slot

2. Wide Camera

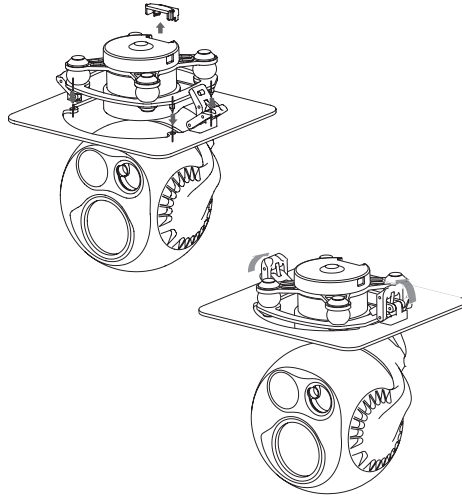
4. Laser Range Finder

6. Control Port



# Installation

1. Remove the control port protector.
2. Align and insert the 4 pins into the locating holes of the mount platform. Press down the lock catch to fix the pod. The pod can be also fixed with screws through the holes on the damping platform.
3. Plug the pod control cable into the control port and install the port protector back.



- ⚠ While upward mounted or mounted at carriers with large vibration or impact, the pod should be fixed with screws nor the quick-release locks.
- ⚠ Gently plug or unplug the cable. Avoid hard pull the cable.
- ⚠ Avoid squash the cable while installing the port protector.
- ⚠ Ensure the microSD card slot cover is firmly in place to prevent dust or moisture entering during usage or storage.
- ⚠ The pod heats while operating. Please ensure the device good cooling.
- ⚠ Do not hard-connect the pod to the carrier, and make sure that the pod does not come into contact with the carrier during use.
- 🔍 The MicroSD card should be configured as HDD-FAT32 mode.

## Configuring & Upgrading Firmware

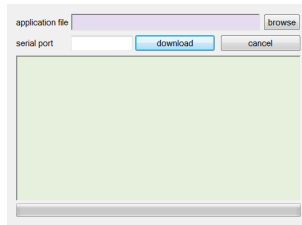
-  Ensure the gimbal and the GCU have both been upgraded to the latest firmware before use. Otherwise, usage may be affected.
-  Ensure the driver of the config module is installed on the computer before configuring or upgrading the firmware.
-  Before configuring, the computer should be set to a static IP address, which is in the same network segment with the GCU and the camera (without IP address conflicts). The default IP address of the GCU and the camera are 192.168.144.121 and 192.168.144.108.
-  Do not power off the device while upgrading the firmware. Restart the device once firmware upgrade is complete.

1. Connect the computer and ETH port with the Network Conversion Module. Power on the devices.
2. Run the Dragonfly display and control software to confirm that it is connected to the pod. Open the settings page.
3. When the settings are complete, click "Save".
4. Restart the pod to enable the configurations to take effect.

-  For instructions on Net Settings, CAMERA, S.BUS Setting, Calibration, Carrier, and Advance, please refer to the 《Dragonfly Quick Start Guide》 - Ribbon - Settings, or visit the [www.allxianfei.com](http://www.allxianfei.com) to get information in the Video Center.

## GCU Upgrading

1. Connect the computer and UART port of the GCU with the config module. Power on the devices.
2. Run FreeFlightIAP software. Choose the COM port corresponding to the config module.
3. Click "browse", choose the firmware file, click "download" and wait for the upgrading complete.



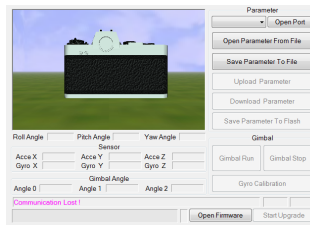
For more information, please refer to the 《GCU User Manual》, Visit the [www.allxianfei.com](http://www.allxianfei.com) to obtain information in the Video Center.

## Gimbal Upgrading

1. Connect the pod and the GCU with the pod control cable. Connect the computer and the gimbal upgrade port with the config module. Power on the devices.
2. Run GimbalConfig software. Choose the COM port corresponding to the config module. Click "Open Firmware", choose the firmware file, click "Start Upgrade" and wait for the upgrading complete.



For some brands of dual Type-C cables, there may be cases where the computer cannot recognize the Config Module. Please try replacing it with a Type-A to Type-C cable.



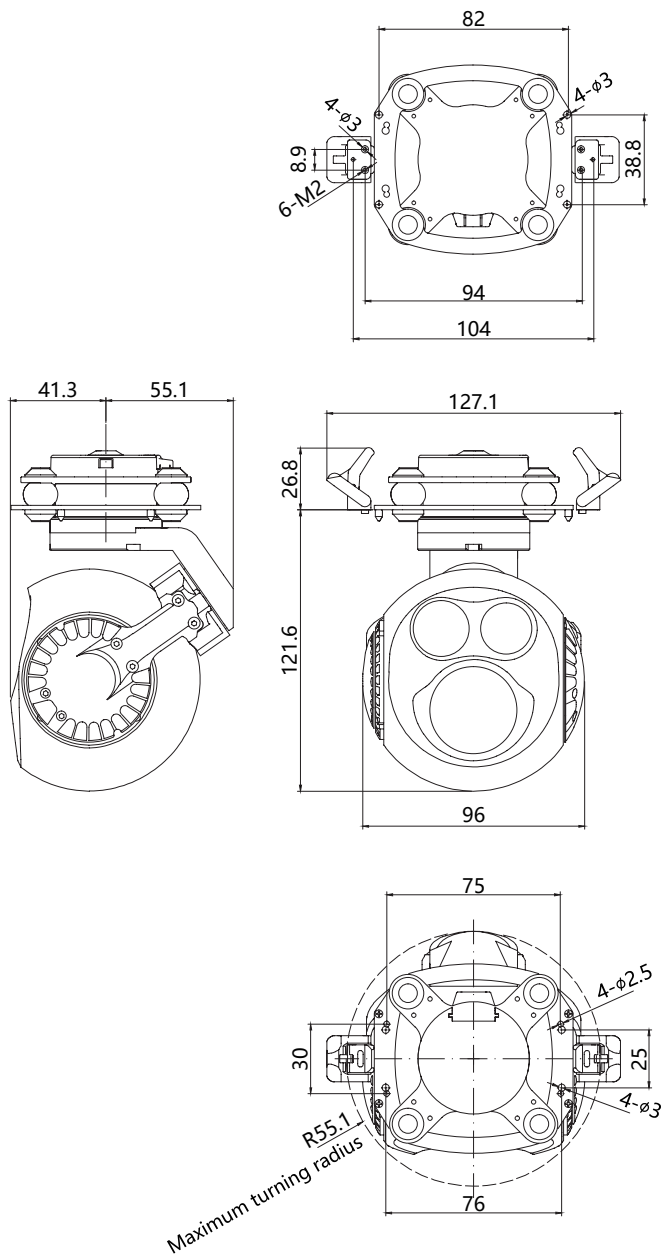
Visit the [www.allxianfei.com](http://www.allxianfei.com) for more information in the Video Center.

## Real-time Video Playing

Example as camera IP address 192.168.144.108:

Stream address: `rtsp://192.168.144.108/554`

# Appendix 1 Dimensions



Unit: mm

## Appendix 2 SEI Data Structure

typedef struct // 64 bytes. Little-endian byte order. Byte alignment

```
{
    uint8_t head[2]; // Header [0xEE, 0x16]
    struct
    {
        uint8_t rng_trig:1; // Ranging trigger flag
        uint8_t pip_state:3; // Pic-in-Pic Statue
                                0-Zoom camera (main)+Wide camera (sub);
                                1-Wide camera;
                                2-Wide camera (main)+ Zoom camera (sub);
                                3-Zoom camera
        uint8_t data_valid:1; //Validity flag of carrier's coordinate, carrier's attitude
                                and camera's attitude
        uint8_t tgt_valid:1; //Validity flag of target's coordinate
        uint8_t reserved:2; // Reserved flag
    } flag;
    int32_t uav_lon; // Longitude of carrier. [-180°, 180°). Resolution 1e-7deg
    int32_t uav_lat; // Latitude of carrier. [-90°, 90°]. Resolution 1e-7deg
    int32_t uav_alt; // Altitude of carrier. Resolution 1mm
    int32_t uav_hgt; // Relative height of carrier. Resolution 1mm
    int16_t uav_phi; // Roll angle of carrier. [-180°, 180°). Resolution 0.01deg
    int16_t uav_the; // Pitch angle of carrier. [-90°, 90°]. Resolution 0.01deg
    uint16_t uav_psi; // Yaw angle of carrier. [0°, 360°). Resolution 0.01deg
    int16_t cam_phi; // Roll angle of camera. [-90°, 90°]. Resolution 0.01deg
    int16_t cam_the; // Pitch angle of camera. [-180°, 180°). Resolution 0.01deg
    uint16_t cam_psi; // Yaw angle of camera. [0°, 360°). Resolution 0.01deg
    uint16_t cam1_zoom; // Zoom rate of zoom camera. Resolution 0.01x
    uint16_t cam2_zoom; // Zoom rate of wide camera. Resolution 0.01x
    uint16_t rng_dist; // Distance from target. Resolution 0.1m (Invalid, 0)
    uint16_t gnss_week; //GNSS week
    uint32_t gnss_itow; //GNSS microsecond. Resolution 1ms
    int32_t tgt_lon; // Longitude of target. [-180°, 180°). Resolution 1e-7deg (Invalid, 0)
    int32_t tgt_lat; // Latitude of target. [-90°, 90°]. Resolution 1e-7deg (Invalid, 0)
    int32_t tgt_alt; // Altitude of target. Resolution 1mm (Invalid, 0)
    uint16_t cam1_f1x; // Focal length of zoom camera at 1x. Resolution 0.01mm
    uint16_t cam2_f1x; // Focal length of wide camera at 1x. Resolution 0.01mm
    uint8_t reserved[4]; // Reserved
    uint8_t check_sum; // Checksum
} SdSei_t;
```

## Appendix 3 MAVLink Configuration

### ArduPilot

|                  |                                  |
|------------------|----------------------------------|
| <b>SERIAL1</b>   |                                  |
| SERIAL1_BAUD     | 115                              |
| SERIAL1_OPTIONS  | 1024                             |
| SERIAL1_PROTOCOL | 2                                |
| <b>SR1</b>       |                                  |
| SR1_ADSB         | 0 Hz                             |
| SR1_EXIT_STAT    | 0 Hz                             |
| SR1_EXTRA1       | 0 Hz                             |
| SR1_EXTRA2       | 0 Hz                             |
| SR1_EXTRA3       | 0 Hz                             |
| SR1_PARAMS       | 0 Hz                             |
| SR1_POSITION     | 0 Hz                             |
| SR1_RAW_CTRL     | 0 Hz                             |
| SR1_RAW_SENS     | 0 Hz                             |
| SR1_RC_CHAN      | 0 Hz                             |
| <b>MNT1</b>      |                                  |
| MNT1_TYPE        | 4 (Gremsy) / 6 (SToRM32 Mavlink) |
| <b>RC1</b>       |                                  |
| RC1_OPTION       | 213 (MOUNT1_PITCH)               |
| <b>RC2</b>       |                                  |
| RC2_OPTION       | 214 (MOUNT1_YAW)                 |
| <b>RC3</b>       |                                  |
| RC3_OPTION       | 163 (MOUNT1_LOCK)                |
| <b>CAM</b>       |                                  |
| CAM_TRIGG_TYPE   | 3 (Mount)                        |

-  The MNT1\_TYPE is recommended as 6. The MNT1\_ROLL\_MAX, MNT1\_ROLL\_MIN, MNT1\_PITCH\_MAX, MNT1\_PITCH\_MIN, MNT1\_YAW\_MAX and MNT1\_YAW\_MIN will be configured automatically depend on data from the GCU. The angle limit should be set manual while the MNT1\_TYPE is 4.
-  The RC1~RC3 are just examples, which can be defined according to actual situation.

## PX4

| MAVLink           |                                                   |
|-------------------|---------------------------------------------------|
| MAV_1_CONFIG      | TELEM2                                            |
| MAV_1_MODE        | Custom / Gimbal                                   |
| MAV_1_RATE        | 115200 B/s                                        |
| Serial            |                                                   |
| SER_TEL2_BAUD     | 115200 8N1                                        |
| Mount             |                                                   |
| MNT_MAIN_PITCH    | AUX1                                              |
| MNT_MAIN_YAW      | AUX2                                              |
| MNT_MODE_IN       | Auto (RC and Mavlink Gimbal)                      |
| MNT_MODE_OUT      | MAVLink gimbal protocol v2                        |
| Camera Setup      |                                                   |
| Trigger mode      | Distance based, on command (Survey mode)          |
| Trigger interface | MAVLink (forward via MAV_CMD_IMAGE_START_CAPTURE) |

-  The MAV\_1\_MODE is recommended as Custom.
-  The AUX1 and AUX2 are just examples, which can be defined according to actual situation. It should be configured in RC Map for further application.
-  The trigger mode is just an example, which can be modified according to actual situation.



## Appendix 4 MAVlink Communication Process

After receiving HeartBeat from the flight controller, and identifying SYSID and COMPID of the flight controller, GCU will operate as below:

1. GCU actively sends package *MAVLINK\_MSG\_ID\_HEARTBEAT 0* at a frequency of 2Hz.
2. GCU requests following packages in turn at a frequency of 1Hz. The flight controller fills these parameters into package *MAVLINK\_MSG\_ID\_COMMAND\_LONG 76* until the request completing.:  
*MAVLINK\_MSG\_ID\_EKF\_STATUS\_REPORT 193 (No this package for PX4);*  
*MAVLINK\_MSG\_ID\_GLOBAL\_POSITION\_INT 33;*  
*MAVLINK\_MSG\_ID\_SCALED\_IMU 26;*  
*MAVLINK\_MSG\_ID\_SYSTEM\_TIME 2;*  
*MAVLINK\_MSG\_ID\_RC\_CHANNELS 65;*  
*MAVLINK\_MSG\_ID\_CAMERA\_TRIGGER 112 (No this package for APM);*  
*MAVLINK\_MSG\_ID\_AUTOPILOT\_STATE\_FOR\_GIMBAL\_DEVICE 286;*  
*MAVLINK\_MSG\_ID\_GIMBAL\_DEVICE\_SET\_ATTITUDE 284 (No this package for APM);*
3. GCU actively sends package *MAVLINK\_MSG\_ID\_GIMBAL\_DEVICE\_ATTITUDE\_STATUS 285* at a frequency of 100 Hz while the packages above being received and the pod being operational.
4. Generally, the flight controller will request package *MAVLINK\_MSG\_ID\_GIMBAL\_DEVICE\_INFORMATION 283*, which GCU does not send actively.