🇬🇧 Operating instructions

X3 Mini Gimbal PRO Software
No. 10010RC

INTENDED USE

> **i** Please download the latest version of the operating instructions from our website at www.rclogger.com. Navigate to the product page and open the "Downloads" tab. Click on "Operating instructions" to start the download.

> ✔ Make this product available to third parties only together with its operating instructions.

This software manual guides you through the calibration of the X3 Mini Gimbal's software. You will learn how to make necessary adjustments on your computer and how to adjust parameters of the gimbal software.

Make sure you attentively, precisely and sequentially follow all steps. Otherwise, the configuration may fail, or the gimbal may behave unpredictably.

WHAT YOU NEED

> X3 Mini Gimbal (10010RC)
> USB adapter (supplied with 10010RC)
> Micro USB cable (supplied with 10010RC)
> Computer running Windows® XP, 7, 8, 8.1, 10
> Operating instructions

BEFORE YOU START

> ✔ Have the installation instructions ready that came with the X3 Mini Gimbal. Refer to them whenever there is need.

> Install the gimbal on your model.
> Ensure that the model stands on a flat and horizontal surface, free from vibrations.
> Note that a USB cable solely designed for charging cannot be used.
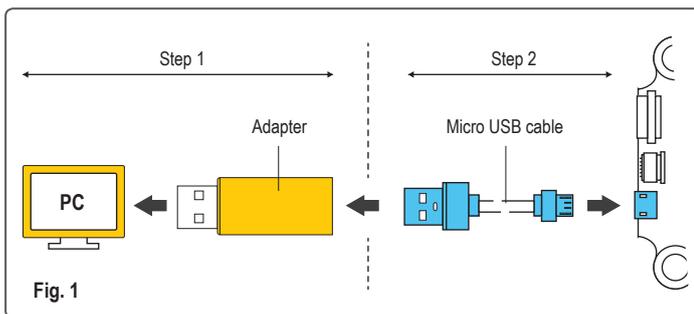
GETTING THE SOFTWARE READY

> ✔ At this stage, do not supply the gimbal with power.

1. Download the zipped X3 Mini Gimbal software file from www.rclogger.com and unzip it.
2. Install the USB-UART Bridge driver **'CP210xVCPInstaller'**. Follow the installer instructions.
   » CP210xVCPInstaller_x64.exe for 64 bit Windows® OS
   » CP210xVCPInstaller_x86.exe for 32 bit Windows® OS
3. It may be necessary to restart your computer after installing the driver.
4. Connect the USB adapter to a free USB port on your computer (see Fig.1, step 1).
5. Open the **Device Manager** on your computer.
6. Check the port number assigned to the adapter ('USB to UART Bridge') (Fig. 2). If the port number is larger than 10, assign a new port number that is no larger than 10.
7. Set –Bits per second– to –115200 bps– (Fig. 3).
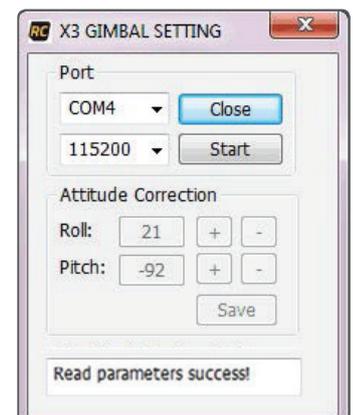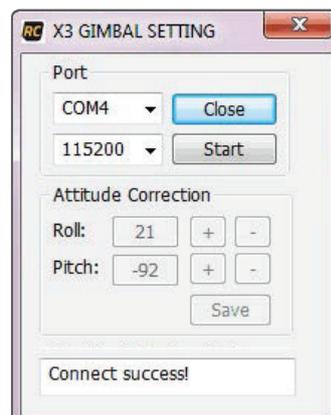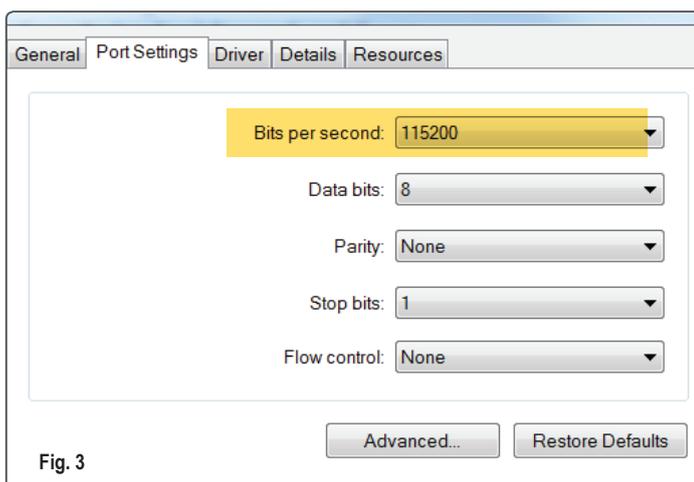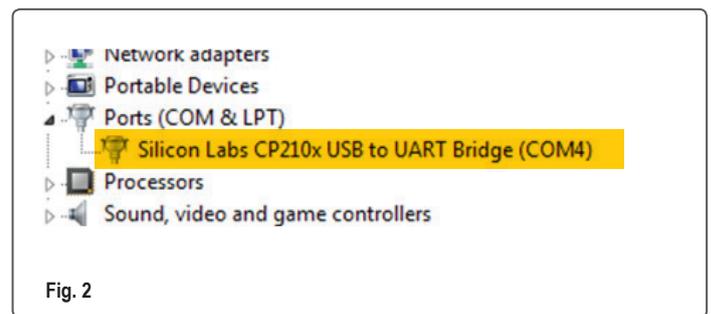8. Save settings.
9. A restart of your computer may be required.

SOFTWARE CONFIGURATION

1.1 Important notes

> If you intend to configure pitch/roll and heading following mode, configure pitch/roll first.
> Pitch/roll and heading following mode have individual –Save– buttons. Therefore, save buttons must be pressed individually when applying settings.
> When saving parameters to the gimbal, the gimbal motors may run. Ensure that the gimbal is installed properly on the model before you start the configuration.

1.2 Ready gimbal for configuration

1. Connect the micro USB cable to the USB adapter. Connect the micro USB plug to the gimbal (see Fig.1, step 2). Ensure that the gimbal stays static and is not exposed to vibrations.
2. Open the downloaded **X3 Mini Gimbal Setting.exe** file to start the gimbal configuration software. You will be presented with the software interface.
3. Select the correct port number and set –Bits per second– to –115200 bps–.
4. Click on –Open– to open the port.
5. Supply power to the gimbal.

Step 1 — Adapter — Step 2 — Micro USB cable — PC

Fig. 1

Network adapters
Portable Devices
Ports (COM & LPT)
 Silicon Labs CP210x USB to UART Bridge (COM4)
Processors
Sound, video and game controllers

Fig. 2

General | Port Settings | Driver | Details | Resources

Bits per second: 115200
Data bits: 8
Parity: None
Stop bits: 1
Flow control: None

Advanced... | Restore Defaults

Fig. 3

X3 GIMBAL SETTING
Port
COM4 | Close
115200 | Start
Attitude Correction
Roll: 21 | + | -
Pitch: -92 | + | -
Save
Connect success!

Fig. 4

X3 GIMBAL SETTING
Port
COM4 | Close
115200 | Start
Attitude Correction
Roll: 21 | + | -
Pitch: -92 | + | -
Save
Read parameters success!

Fig. 5

6. After successful connection, the software interface shows –*Connect success!*– (Fig. 4).

7. The gimbal will now launch a self-inspection procedure to initialize the gyroscope. Wait for the message –*Read parameters success!*–. The current parameters are displayed in the software interface (Fig. 5).

8. Continue with configuration of pitch, roll and heading.

1.3 Configuring pitch and roll

Roll correction   **Pitch correction**
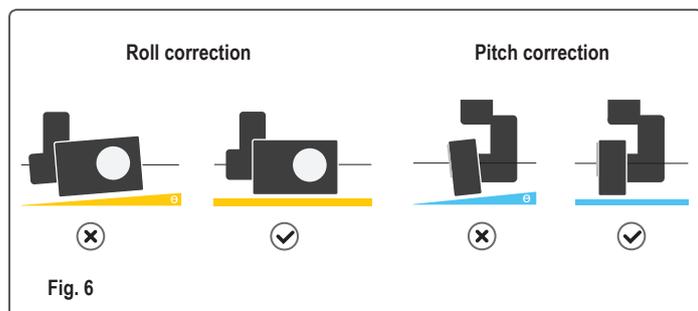
Fig. 6

With the attitude (roll, pitch) settings you correct/adjust roll and pitch angles. Refer to Fig. 6 that illustrates angle adjustment. Make use of an angle gauge when adjusting the angles.

Do the following to adjust/correct the pitch and roll angle:

1. In the interface click on –*Start*– and wait for the gimbal motors to enter the working modus.

2. Correct the roll angle with the *(+)* and *(–)* buttons next to –*Roll:–*.

3. Correct the pitch angle with the *(+)* and *(–)* buttons next to –*Pitch:–*.

4. Click on –*Save*– to save the new angle configurations and wait until –*Save parameters success!*– is displayed.

5. Click on –*Stop*–, then –*Close*– to close the port.

6. Close the software window.

7. Disconnect the power supply.

8. Disconnect the USB cable.

9. The gimbal is ready for use again.

PRODUCT SUPPORT

Visit http://www.rclogger.com/support or call +852 2559 2662 for product support. Additionally visit our Online Ticket System at http://support.rclogger.com for any RC Logger inquiry.

TECHNICAL DATA

Operating system compatibility.................................Windows® XP, 7, 8, 8.1, 10