

General Description

The Mercury-G4 is a flight controller (FC) designed for small, manually-controlled quadcopters and fixed-wing aircraft. It can be mounted into frames that include 30.5×30.5mm or 20×20mm square mounting patterns that fit M3 (3mm diameter) or M2 (2mm diameter) screws respectively. It includes a STM32G473 microcontroller preinstalled with Betaflight firmware. iNav support is coming soon. To work with fixed-wing aircraft (or any use with servos), Mercury G4 requires an external 5V voltage regulator (aka *BEC*).

Mercury is designed to be connected to motors via a DSHOT-capable Electronic Speed Controller (ESC), and a digital video transmitter (eg DJI, HDZero, Walksnail etc). It can also be connected to an external Global Navigation Satellite System (GNSS) such as GPS, a magnetometer, and other sensors. The FC provides JST SH and GH connectors for this purpose. Additionally, there are labeled solder pads on the top of the flight controller than may be used in lieu of these connectors. Sections below provide details on connecting to these systems.

Mercury is designed to be used with digital video systems only: It provides no analog on-screen-display functionality.

Mercury includes a full ExpressLRS (ELRS) control receiver radio, with a dedicated microcontroller that runs official ELRS firmware.

Important: **Do not use Mercury with a battery voltage higher than 26V.** This means, no more than a 6S (3.7v LiPo) battery. In order to be used with DJI or HDZero Vtx systems, use no smaller than a 3S battery. This means the battery cell count must be between 3S and 6S.

Specifications

- **Dimensions:** 34×34×6 (height) mm
- **Weight:** 14 grams
- **Mounting holes:** M3 (3mm diameter). 30.5mm × 30.5mm, and 20mm × 20mm square patterns
- **Power:** 6V– 26V (2-6S LiPo. Digital Vtxes require 7V, so use a 3-6S LiPo)
- **MCU:** STM32G473. 170Mhz Cortex-M4, 512Kbyte internal flash, 128kb SRAM
- **Inertial Measurement Unit (IMU):** TDK ICM-42688p
- **Barometer (pressure altimeter):** Infineon DPS-310
- **Storage:** 16Mbit "black box" flash: W25Q16

- **Power and flashing:** USB-C (DFU), and SWD
- **ESC pin header:** JST GH, 1.25mm pitch, 8 pins (Diatone layout)
- **Digital Vtx / cam pin header:** JST SH, 1mm pitch, 6 pins, (DJI layout)
- **Free UART connections:** 3. (UART2 and UART4 are dedicated to ELRS Rx and digital OSD respectively; UART1, UART3, and LPUART1 may be used for external devices)
- **I²C buses:** 1
- **Control radio receiver:** Semtech SX1280. (Compatible with ELRS transmitters)
- **Power pad voltages:** VBAT, 5V, 3.3V
- **Current capacity:** 1.2A on the 5V line. 500MA on the 3.3V line.
- **Voltage limiter:** 26V TVS diode

Connecting to an ESC

When used for quadcopters, Mercury is designed to work with a "4-in-1" Electronic Speed Controller (ESC). This ESC is responsible for supplying power to the aircraft via a battery connected to it, and for controlling signals sent to brushless motors, also connected directly to the ESC. This ESC should use the DSHOT protocol to receive power commands from the FC, and send measured RPM back to the FC along the same line.

When used for fixed-wing aircraft, the ESC is likely to only need connections to 1 or 2 motors, so a single-motor ESC may be sufficient. A DSHOT-capable ESC is recommended, but PWM ESCs work as well. PWM ESCs are sufficient for the update rates required for the thrust-providing propellers used on fixed-wing aircraft, but lack the signal robustness and error-checking functionality of DSHOT.

To connect to an ESC, use either the 8-pin ESC connect (JST SH: 1mm pitch) on the bottom of the FC, or the solder pads labeled "ESC" on the top. This header and these pads contain the following connections. Note that these are in the same order as Diatone FCs. They are in the *reverse order* of Diatone ESC connections. The colors labeled below apply to the included cables.

It may help cable management to twist the ESC connector cable a few times.

- **Ground.** (black) This is connected to the battery's negative (black) terminal, and provides a common ground voltage reference for the entire aircraft. Passed-through by the ESC.

- **Battery** in (+Bat). (red) This is connected to the battery's positive (hot) terminal, and is nominally 7.4 to 22.2V, depending on battery cell count. This, stepped down to various lower voltages (mainly 3.3V) provides power to all systems on the aircraft connected to the FC.

- **Motors 1-4.** (white) This is used to send motor power commands via DSHOT from the FC to the ESC, and for the ESC to send RPM measurements to the FC.

- **ESC telemetry.** (blue) This provides data from the ESC to the flight controller over a UART channel. It is connected to the UART3 Rx line on Mercury. It typically provides ESC temperature, and RPM data. The RPM data is typically at a lower update rate than that provided by DSHOT. To use in firmware (eg Betaflight), configure your firmware to use ESC telemetry on UART3. This connection is optional.

- **ESC current.** (orange) This outputs a voltage proportional to the total current consumed by the ESC at a given time. It is passed through a 11:1 voltage divider before connecting to the FC's ADC. The Betaflight config has this scaler value included by default; it is provided here for reference. This connection is optional.

Mercury comes with 2 ESC connection wire assemblies: One for use with Diatone ESCs, and one that has bare wires, for soldering to pads.

Connecting a digital video transmission system

Mercury is intended to be used with a digital video transmissions system, such as DJI/Caddx, HDZero, and WalkSnail. These connect to Mercury using a 6-pin JST SH (1mm pitch) pin header or 6 solder pads, both on the top of the FC. These have the following connections:

- **Battery in** (+VBat). Note that Mercury doesn't have a dedicated voltage regulator for the video transmitter; it passes the battery voltage through, after passing through a TVS diode that limits voltage spikes; no-more-than 26 volts ever passes through this pad. Note that at least 7V of the battery must be available to support DJI and HDZero systems.

- **Ground** (to power the camera and transmitter),

- **UART 2 Rx and Tx** connections (To receive information to populate the On-Screen Display (OSD)).

- **A second ground connection**, for use with DJI radio controllers. Optional.

- **A UART 1 Rx HDL data connection**, for use with DJI radio controllers. Optional. If using this line, don't connect anything to the *Rx1* solder pad in the UART section of the FC.

To connect to a Vtx/cam, use either the 6-pin ESC header (JST SH: 1mm pitch) on the top of the FC, or the pads labeled "Vtx/Cam" on the top. The *HDL* and its adjacent ground connection are optional: These are for use with DJI radio controllers.

Mercury comes with 2 Btx connection wire assemblies: One for use with DJI digital (eg DJI O3), and one that has bare wires, for soldering to pads.

Connecting to an external radio receiver

Mercury is compatible with ELRS transmitters using no external hardware.

If you wish to use an external radio receiver, connect the receiver to Mercury using a groundwire soldered to a ground pad, a power wire connected to a power +5V pad, and a UART Tx/Rx pair. (Only Rx is required for normal operation).

Configuring your radio transmitter

The Betaflight firmware that comes with your flight controller is automatically configured to work with the onboard ELRS receiver. Updating using the Betaflight *Configurator* also automatically configures the receiver, so no special action is required.

As a confirmation, this is what you should see on the *Configurator ports* section:
(todo: Screenshot)

This is what you should see in the *receiver* section:
(todo: screenshot)

Using an external BEC for servos

The 5V power connectors on Mercury don't provide enough current capacity for use with servos. To connect servos, you need to use an external regulator. This can be connected to the battery terminal on the ESC, or the *Vbat* solder pad on the FC. Connect the servo's 5V line to this, and the servo's signal line to one of the FC's motor connections. (Connector, or solder pad)

Using with Betaflight

Mercury supports Betaflight, version 4.3 and higher. It is compatible with quadcopters, but not fixed-wing aircraft. To flash with BetaFlight, the first step is to start your FC in DFU mode. To do this, hold the button on the FC down, while applying, or resetting power. (eg plugging in the USB cable).

- Connect the FC to a PC that has the Betaflight Configurator installed.
- Using the tab at the top, select *Flash firmware*.
- Select *AnyLeaf Mercury G4* flight controller from the list.
- At the bottom of the screen, select *Load online*.
- Select *Flash firmware*. Wait for the flashing to complete.

Note that this configuration automatically configures the ELRS radio, and the digital display OSD on UART2. To connect to an external radio receiver, configure manually using the Ports and Radio tabs.

The default Betaflight config configures Mercury G4 to use a 4kHz PID loop, and DSHOT 300 (300kHz). If your ESC is compatible, we recommend you enable bidirectional DSHOT. If you leave bidirectional DSHOT disabled, you can use DSHOT600. The config sets up "Bitbanged" DSHOT, instead of Burst DMA. Burst DMA appears, as of the latest Betaflight, to be incompatible with bidirectional DSHOT.

Here's an example of the *Ports* tab in Betaflight, showing how to configure with an OSD, the onboard ELRS Rx, and GPS. Note that Mercury will set up UART2 (ELRS Rx), and UART4 (OSD) by default as shown. If you use a GPS, make sure to set the *Sensor Input* column to *GPS / AUTO*, and depicted below:

Identifier	Configuration/MSP	Serial Rx	Telemetry Output	Sensor Input
USB VCP	<input checked="" type="checkbox"/> 115200 ▾	<input type="checkbox"/>	Disabled ▾ AUTO ▾	Disabled ▾ AUTO ▾
UART1	<input type="checkbox"/> 115200 ▾	<input type="checkbox"/>	Disabled ▾ AUTO ▾	GPS ▾ AUTO ▾
UART2	<input type="checkbox"/> 115200 ▾	<input checked="" type="checkbox"/>	Disabled ▾ AUTO ▾	Disabled ▾ AUTO ▾
UART3	<input type="checkbox"/> 115200 ▾	<input type="checkbox"/>	Disabled ▾ AUTO ▾	Disabled ▾ AUTO ▾
UART4	<input checked="" type="checkbox"/> 115200 ▾	<input type="checkbox"/>	Disabled ▾ AUTO ▾	Disabled ▾ AUTO ▾
LPUART1	<input type="checkbox"/> 115200 ▾	<input type="checkbox"/>	Disabled ▾ AUTO ▾	Disabled ▾ AUTO ▾

The image below is from Betaflight's *Receiver* tab. Note that the protocol is configured to be Serial, using the CRSF provider. Telemetry is enabled, and the RSSI channel is set to AUX 11. AUX 11 corresponds to Link Quality. This is done due to a limitation on some DJI OSDs, where only 1 receiver statistic can be shown. (As configured on the OSD tab as "RSSI value"). If you wish to show RSSI instead, set this to AUX 12.

Receiver

Serial (via UART) ▼

Receiver Mode

- The UART for the receiver must be set to 'Serial Rx' (in the Ports tab)
- Select the correct data format from the drop-down, below:

CRSF ▼

Serial Receiver Provider

Telemetry ?

TELEMETRY

Telemetry output

RSSI (Signal Strength) ?

RSSI_ADC

Analog RSSI input

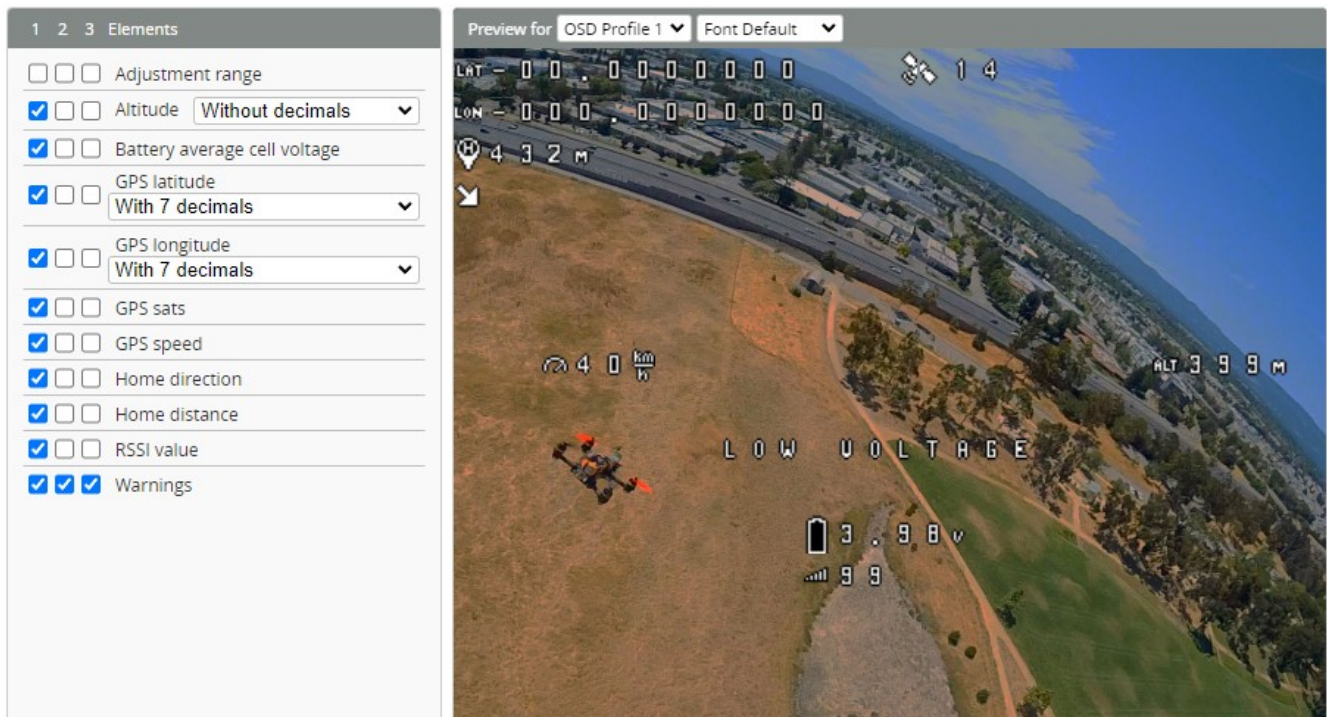
Channel Map

RSSI Channel

AETR1234 ▼

AUX 11 ▼

An example Betaflight OSD config with DJI Vista or Air Unit is shown below. This is an example of useful information to display given its limited set of OSD features. If using DJI O3 or HDZero, you may have be able to select more options. (Many options you select will simply fail to show on the goggles when using Vista or Air Unit). Unlike the settings above, this *is not* set up by default; you must configure the OSD items manually.



Power delivery

Mercury G4 has 5V and 3.3V power lines exposed. The 5V line supports 1.2A of current. The 5V and 3.3V lines may be used with external hardware, like GPS and time-of-flight sensors. Note that the current capacity on the 5v line isn't high enough for most servos; if you wish to use this FC with more than one servo (eg fixed-wing aircraft), an external regulator (BEC) is required.

The IMU's power supply is isolated from other circuitry on the FC using a power filtering circuit that eliminates high-frequency oscillations.

A TVS diode is located between the ESC's battery connection, and the rest of the power delivery lines. This prevents voltage spikes above 26V from reaching the system. While this prevents spikes, it's important not to connect a LiPo battery with more than 6 cells.

Pin Mappings

Mercury uses the following pin assignments:

Connection	MCU Port and pin	MCU peripheral	Notes
Motor 1	PC6	Timer 3, Ch1	
Motor 2	PA4	Timer 3, Ch2	
Motor 3	PB0	Timer 3, Ch3	
Motor 4	PB1	Timer 3, Ch4	
UART1 Tx	PB6		Also exposed on GPS connector
UART1 Rx	PB7		Also exposed as DJI HDL, and the GPS connector
UART2 Tx	PB3		Used for the onboard ELRS receiver; no pad
UART2 Rx	PB4		Used for the onboard ELRS receiver; no pad
UART3 Tx	PB10		
UART3 Rx	PB11		Also exposed as ESC telemetry
UART4 Tx	PC10		Used for Video OSD
UART4 Rx	PC11		Used for Video OSD
LPUART1 Tx	PA2		
LPUART1 Rx	PA3		
I2C1 SDA	PB9		
I2C1 SCL	PA15		
I2C2 SDA	PA8		Used by baro-altimeter; no pad
I2C2 SCL	PA9		Used by baro-altimeter; no pad

Buzzer	PA10	Timer 1, Ch3, or Timer 2, Ch4	This is a PWM signal alternating between ground and 3.3V
Batt voltage ADC	PA1	ADC1 or 2, Ch1	From a voltage divider, with scaling factor 11
Current ADC	PB2	ADC2, Ch12	From a voltage divider, with scaling factor 11

The Vtx/cam pad and header pin labeled "HDL" is the same connection as the UART 1 Rx pad. The ESC telemetry pad and header pin is the same connection as the UART 3 Rx pad. If using the HDL connection, don't use UART1 Rx for anything else; if using ESC telemetry connection, don't use UART 3 Rx for anything else.

Note that there are no exposed SPI pads; both SPI lines are used by FC peripherals (IMU and flash storage).

Support

If you have any questions, or support requests, contact us by email: anyleaf@anyleaf.org.

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