

```
Entering CLI Mode, type 'exit' to return, or 'help' # diff

# version
# Betaflight / KAKUTEF4V2 (KTV2) 3.5.1 Sep 8 2018 / 05:24:58 (d9fb5ca13) MSP API:
1.40

board_name KAKUTEF4V2
manufacturer_id

# name
name Racer

# resources

# mixer

# servo

# servo mix

# feature
feature GPS

# beeper
beeper -GYRO_CALIBRATED
beeper -RX_LOST_LANDING
beeper -DISARMING
beeper -ARMING
beeper -ARMING_GPS_FIX
beeper -BAT_CRIT_LOW
beeper -BAT_LOW
beeper -RX_SET
beeper -ACC_CALIBRATION
beeper -ACC_CALIBRATION_FAIL
beeper -READY_BEEP
beeper -DISARM_REPEAT
beeper -ARMED
beeper -SYSTEM_INIT
beeper -ON_USB
beeper -BLACKBOX_ERASE

# beacon

# map
map TAER1234

# serial
serial 0 0 115200 57600 0 115200
serial 5 2 115200 115200 0 115200

# led

# color

# mode_color

# aux
aux 0 0 0 900 1550 0 0
aux 1 1 0 1300 1700 0 0
aux 2 2 0 900 1400 0 0
aux 3 6 2 900 1700 0 0
aux 4 27 1 1625 2100 0 0
aux 5 28 3 900 1550 0 0
```

```
# adjrange

# rxrange

# vtx

# rxfail
rxfail 4 s 1350

# master
set gyro_use_32khz = ON
set dyn_notch_quality = 5
set dyn_notch_width_percent = 20
set mag_hardware = NONE
set rc_smoothing_type = FILTER
set fpv_mix_degrees = 25
set dshot_idle_value = 2000
set motor_pwm_protocol = DSHOT600
set failsafe_delay = 200
set failsafe_throttle = 1350
set failsafe_throttle_low_delay = 200
set failsafe_procedure = AUTO-LAND
set bat_capacity = 1550
set vbat_max_cell_voltage = 42
set vbat_min_cell_voltage = 37
set current_meter = ADC
set small_angle = 180
set gps_provider = UBLOX
set gps_sbas_mode = EGNOS
set gps_auto_baud = ON
set gps_rescue_sanity_checks = RESCUE_SANITY_OFF
set pid_process_denom = 2
set osd_alt_alarm = 500
set osd_vbat_pos = 2166
set osd_rssi_pos = 184
set osd_tim_1_pos = 2551
set osd_tim_2_pos = 2519
set osd_remaining_time_estimate_pos = 449
set osd_flymode_pos = 2541
set osd_vtx_channel_pos = 473
set osd_crosshairs_pos = 2285
set osd_ah_sbar_pos = 2286
set osd_ah_pos = 2158
set osd_current_pos = 420
set osd_mah_drawn_pos = 2199
set osd_gps_speed_pos = 248
set osd_gps_lon_pos = 2064
set osd_gps_lat_pos = 2050
set osd_gps_sats_pos = 2489
set osd_home_dir_pos = 2102
set osd_home_dist_pos = 2103
set osd_compass_bar_pos = 449
set osd_altitude_pos = 2145
set osd_power_pos = 2178
set osd_warnings_pos = 2345
set osd_battery_usage_pos = 480
set osd_disarmed_pos = 395
set osd_nvario_pos = 216
set osd_rtc_date_time_pos = 418
set osd_stat_rtc_date_time = ON
set osd_stat_max_dist = ON
set osd_stat_max_alt = ON
```

```
# profile
profile 0

set dterm_notch_cutoff = 0
set vbat_pid_gain = ON
set anti_gravity_threshold = 350
set iterm_rotation = OFF
set iterm_relax = RP
set iterm_relax_type = SETPOINT
set iterm_relax_cutoff = 9
set throttle_boost = 10
set f_pitch = 100
set f_roll = 100
set p_yaw = 40
set i_yaw = 120
set f_yaw = 100
set abs_control_gain = 10
```

```
# rateprofile
rateprofile 0
```

```
set roll_rc_rate = 160
set pitch_rc_rate = 160
set yaw_rc_rate = 160
set roll_expo = 30
set pitch_expo = 30
set yaw_expo = 11
set roll_srate = 90
set pitch_srate = 90
```