

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

# 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

resource BEEPER 1 C09

resource MOTOR 1 B00

resource MOTOR 2 B01

resource MOTOR 3 A03

resource MOTOR 4 A02

resource MOTOR 5 NONE

resource MOTOR 6 NONE

resource MOTOR 7 NONE

resource MOTOR 8 NONE

resource SERVO 1 NONE

resource SERVO 2 NONE

resource SERVO 3 NONE

resource SERVO 4 NONE

resource SERVO 5 NONE

resource SERVO 6 NONE

resource SERVO 7 NONE

resource SERVO 8 NONE

resource PPM 1 C07

resource PWM 1 NONE

resource PWM 2 NONE

resource PWM 3 NONE

resource PWM 4 NONE

resource PWM 5 NONE

resource PWM 6 NONE

resource PWM 7 NONE

resource PWM 8 NONE

resource LED\_STRIP 1 C08

resource SERIAL\_TX 1 A09

resource SERIAL\_TX 2 NONE

resource SERIAL\_TX 3 B10

resource SERIAL\_TX 4 A00

resource SERIAL\_TX 5 NONE

resource SERIAL\_TX 6 C06

resource SERIAL\_TX 7 NONE

resource SERIAL\_TX 8 NONE

resource SERIAL\_TX 9 NONE

resource SERIAL\_TX 10 NONE

resource SERIAL\_TX 11 NONE

resource SERIAL\_RX 1 A10

resource SERIAL\_RX 2 NONE

resource SERIAL\_RX 3 B11

resource SERIAL\_RX 4 A01

resource SERIAL\_RX 5 D02

resource SERIAL\_RX 6 C07

resource SERIAL\_RX 7 NONE

resource SERIAL\_RX 8 NONE

resource SERIAL\_RX 9 NONE

resource SERIAL\_RX 10 NONE

resource SERIAL\_RX 11 NONE

resource INVERTER 1 NONE

resource INVERTER 2 NONE

```
resource INVERTER 3 B15
resource INVERTER 4 NONE
resource INVERTER 5 NONE
resource INVERTER 6 NONE
resource INVERTER 7 NONE
resource INVERTER 8 NONE
resource INVERTER 9 NONE
resource INVERTER 10 NONE
resource INVERTER 11 NONE
resource I2C_SCL 1 B08
resource I2C_SCL 2 NONE
resource I2C_SCL 3 NONE
resource I2C_SDA 1 B09
resource I2C_SDA 2 NONE
resource I2C_SDA 3 NONE
resource LED 1 B05
resource LED 2 B04
resource LED 3 B06
resource RX_BIND 1 NONE
resource RX_BIND_PLUG 1 NONE
resource SPI_SCK 1 A05
resource SPI_SCK 2 NONE
resource SPI_SCK 3 C10
resource SPI_MISO 1 A06
resource SPI_MISO 2 NONE
resource SPI_MISO 3 C11
resource SPI_MOSI 1 A07
resource SPI_MOSI 2 NONE
resource SPI_MOSI 3 C12
resource ESCSERIAL 1 C07
resource CAMERA_CONTROL 1 NONE
resource ADC_BATT 1 C03
resource ADC_RSSI 1 C01
resource ADC_CURR 1 C02
resource ADC_EXT 1 NONE
resource BARO_CS 1 NONE
resource COMPASS_CS 1 NONE
resource PINIO 1 NONE
resource PINIO 2 NONE
resource PINIO 3 NONE
resource PINIO 4 NONE
resource USB_MSC_PIN 1 NONE
resource FLASH_CS 1 B03
resource OSD_CS 1 B14
resource SPI_PREINIT_IPU 1 C04
resource SPI_PREINIT_IPU 2 B03
resource SPI_PREINIT_IPU 3 NONE
resource SPI_PREINIT_IPU 4 NONE
resource SPI_PREINIT_IPU 5 NONE
resource SPI_PREINIT_IPU 6 NONE
resource SPI_PREINIT_IPU 7 NONE
resource SPI_PREINIT_IPU 8 NONE
resource SPI_PREINIT_IPU 9 NONE
resource SPI_PREINIT_IPU 10 NONE
resource SPI_PREINIT_IPU 11 NONE
resource SPI_PREINIT_OPU 1 B14
resource SPI_PREINIT_OPU 2 NONE

# mixer
mixer QUADX

mmix reset
```

```
# servo
servo 0 1000 2000 1500 100 -1
servo 1 1000 2000 1500 100 -1
servo 2 1000 2000 1500 100 -1
servo 3 1000 2000 1500 100 -1
servo 4 1000 2000 1500 100 -1
servo 5 1000 2000 1500 100 -1
servo 6 1000 2000 1500 100 -1
servo 7 1000 2000 1500 100 -1
```

```
# servo mix
smix reset
```

```
# feature
feature -RX_PPM
feature -INFLIGHT_ACC_CAL
feature -RX_SERIAL
feature -MOTOR_STOP
feature -SERVO_TILT
feature -SOFTSERIAL
feature -GPS
feature -RANGEFINDER
feature -TELEMETRY
feature -3D
feature -RX_PARALLEL_PWM
feature -RX_MSP
feature -RSSI_ADC
feature -LED_STRIP
feature -DISPLAY
feature -OSD
feature -CHANNEL_FORWARDING
feature -TRANSPONDER
feature -AIRMODE
feature -RX_SPI
feature -SOFTSPI
feature -ESC_SENSOR
feature -ANTI_GRAVITY
feature -DYNAMIC_FILTER
feature RX_SERIAL
feature GPS
feature TELEMETRY
feature OSD
feature ANTI_GRAVITY
feature DYNAMIC_FILTER
```

```
# beeper
beeper -GYRO_CALIBRATED
beeper RX_LOST
beeper -RX_LOST_LANDING
beeper -DISARMING
beeper -ARMING
beeper -ARMING_GPS_FIX
beeper -BAT_CRIT_LOW
beeper -BAT_LOW
beeper GPS_STATUS
beeper -RX_SET
beeper -ACC_CALIBRATION
beeper -ACC_CALIBRATION_FAIL
beeper -READY_BEEP
beeper MULTI_BEEPS
beeper -DISARM_REPEAT
beeper -ARMED
```

```
beeper -SYSTEM_INIT
beeper -ON_USB
beeper -BLACKBOX_ERASE
beeper CRASH_FLIP
beeper CAM_CONNECTION_OPEN
beeper CAM_CONNECTION_CLOSED
beeper RC_SMOOTHING_INIT_FAIL
```

```
# beacon
beacon GYRO_CALIBRATED
beacon -RX_LOST
beacon RX_LOST_LANDING
beacon DISARMING
beacon ARMING
beacon ARMING_GPS_FIX
beacon BAT_CRIT_LOW
beacon BAT_LOW
beacon GPS_STATUS
beacon -RX_SET
beacon ACC_CALIBRATION
beacon ACC_CALIBRATION_FAIL
beacon READY_BEEP
beacon MULTI_BEEPS
beacon DISARM_REPEAT
beacon ARMED
beacon SYSTEM_INIT
beacon ON_USB
beacon BLACKBOX_ERASE
beacon CRASH_FLIP
beacon CAM_CONNECTION_OPEN
beacon CAM_CONNECTION_CLOSED
beacon RC_SMOOTHING_INIT_FAIL
```

```
# map
map TAER1234
```

```
# serial
serial 20 1 115200 57600 0 115200
serial 0 0 115200 57600 0 115200
serial 2 64 115200 57600 0 115200
serial 3 0 115200 57600 0 115200
serial 4 0 115200 57600 0 115200
serial 5 2 115200 115200 0 115200
```

```
# led
led 0 0,0::C:0
led 1 0,0::C:0
led 2 0,0::C:0
led 3 0,0::C:0
led 4 0,0::C:0
led 5 0,0::C:0
led 6 0,0::C:0
led 7 0,0::C:0
led 8 0,0::C:0
led 9 0,0::C:0
led 10 0,0::C:0
led 11 0,0::C:0
led 12 0,0::C:0
led 13 0,0::C:0
led 14 0,0::C:0
led 15 0,0::C:0
led 16 0,0::C:0
led 17 0,0::C:0
led 18 0,0::C:0
```

```
led 19 0,0::C:0
led 20 0,0::C:0
led 21 0,0::C:0
led 22 0,0::C:0
led 23 0,0::C:0
led 24 0,0::C:0
led 25 0,0::C:0
led 26 0,0::C:0
led 27 0,0::C:0
led 28 0,0::C:0
led 29 0,0::C:0
led 30 0,0::C:0
led 31 0,0::C:0
```

```
# color
color 0 0,0,0
color 1 0,255,255
color 2 0,0,255
color 3 30,0,255
color 4 60,0,255
color 5 90,0,255
color 6 120,0,255
color 7 150,0,255
color 8 180,0,255
color 9 210,0,255
color 10 240,0,255
color 11 270,0,255
color 12 300,0,255
color 13 330,0,255
color 14 0,0,0
color 15 0,0,0
```

```
# mode_color
mode_color 0 0 1
mode_color 0 1 11
mode_color 0 2 2
mode_color 0 3 13
mode_color 0 4 10
mode_color 0 5 3
mode_color 1 0 5
mode_color 1 1 11
mode_color 1 2 3
mode_color 1 3 13
mode_color 1 4 10
mode_color 1 5 3
mode_color 2 0 10
mode_color 2 1 11
mode_color 2 2 4
mode_color 2 3 13
mode_color 2 4 10
mode_color 2 5 3
mode_color 3 0 8
mode_color 3 1 11
mode_color 3 2 4
mode_color 3 3 13
mode_color 3 4 10
mode_color 3 5 3
mode_color 4 0 7
mode_color 4 1 11
mode_color 4 2 3
mode_color 4 3 13
mode_color 4 4 10
mode_color 4 5 3
mode_color 5 0 9
```

```
mode_color 5 1 11
mode_color 5 2 2
mode_color 5 3 13
mode_color 5 4 10
mode_color 5 5 3
mode_color 6 0 6
mode_color 6 1 10
mode_color 6 2 1
mode_color 6 3 0
mode_color 6 4 0
mode_color 6 5 2
mode_color 6 6 3
mode_color 6 7 6
mode_color 6 8 0
mode_color 6 9 0
mode_color 6 10 0
mode_color 7 0 3
```

```
# 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
aux 6 0 0 900 900 0 0
aux 7 0 0 900 900 0 0
aux 8 0 0 900 900 0 0
aux 9 0 0 900 900 0 0
aux 10 0 0 900 900 0 0
aux 11 0 0 900 900 0 0
aux 12 0 0 900 900 0 0
aux 13 0 0 900 900 0 0
aux 14 0 0 900 900 0 0
aux 15 0 0 900 900 0 0
aux 16 0 0 900 900 0 0
aux 17 0 0 900 900 0 0
aux 18 0 0 900 900 0 0
aux 19 0 0 900 900 0 0
```

```
# adjrange
```

```
adjrange 0 0 0 900 900 0 0 0 0
adjrange 1 0 0 900 900 0 0 0 0
adjrange 2 0 0 900 900 0 0 0 0
adjrange 3 0 0 900 900 0 0 0 0
adjrange 4 0 0 900 900 0 0 0 0
adjrange 5 0 0 900 900 0 0 0 0
adjrange 6 0 0 900 900 0 0 0 0
adjrange 7 0 0 900 900 0 0 0 0
adjrange 8 0 0 900 900 0 0 0 0
adjrange 9 0 0 900 900 0 0 0 0
adjrange 10 0 0 900 900 0 0 0 0
adjrange 11 0 0 900 900 0 0 0 0
adjrange 12 0 0 900 900 0 0 0 0
adjrange 13 0 0 900 900 0 0 0 0
adjrange 14 0 0 900 900 0 0 0 0
```

```
# rxrange
```

```
rxrange 0 1000 2000
rxrange 1 1000 2000
rxrange 2 1000 2000
rxrange 3 1000 2000
```

```
# vtx
```

```
vtx 0 0 0 0 900 900
vtx 1 0 0 0 900 900
vtx 2 0 0 0 900 900
vtx 3 0 0 0 900 900
vtx 4 0 0 0 900 900
vtx 5 0 0 0 900 900
vtx 6 0 0 0 900 900
vtx 7 0 0 0 900 900
vtx 8 0 0 0 900 900
vtx 9 0 0 0 900 900
```

```
# rxfail
rxfail 0 a
rxfail 1 a
rxfail 2 a
rxfail 3 a
rxfail 4 s 1350
rxfail 5 h
rxfail 6 h
rxfail 7 h
rxfail 8 h
rxfail 9 h
rxfail 10 h
rxfail 11 h
rxfail 12 h
rxfail 13 h
rxfail 14 h
rxfail 15 h
rxfail 16 h
rxfail 17 h
```

```
# master
set align_gyro = DEFAULT
set gyro_hardware_lpf = NORMAL
set gyro_32khz_hardware_lpf = NORMAL
set gyro_sync_denom = 1
set gyro_lowpass_type = PT1
set gyro_lowpass_hz = 100
set gyro_lowpass2_type = PT1
set gyro_lowpass2_hz = 300
set gyro_notch1_hz = 0
set gyro_notch1_cutoff = 0
set gyro_notch2_hz = 0
set gyro_notch2_cutoff = 0
set gyro_calib_duration = 125
set gyro_calib_noise_limit = 48
set gyro_offset_yaw = 0
set gyro_overflow_detect = ALL
set yaw_spin_recovery = ON
set yaw_spin_threshold = 1950
set gyro_use_32khz = ON
set dyn_notch_quality = 5
set dyn_notch_width_percent = 20
set align_acc = DEFAULT
set acc_hardware = AUTO
set acc_lpf_hz = 10
set acc_trim_pitch = 0
set acc_trim_roll = 0
set acc_calibration = 0,0,0
set align_mag = DEFAULT
set mag_bustype = I2C
set mag_i2c_device = 1
set mag_i2c_address = 0
set mag_spi_device = 0
```

```
set mag_hardware = NONE
set mag_declination = 0
set mag_calibration = 0,0,0
set baro_bustype = I2C
set baro_spi_device = 0
set baro_i2c_device = 1
set baro_i2c_address = 0
set baro_hardware = AUTO
set baro_tab_size = 21
set baro_noise_lpf = 600
set baro_cf_vel = 985
set baro_cf_alt = 965
set mid_rc = 1500
set min_check = 1050
set max_check = 1900
set rssi_channel = 0
set rssi_src_frame_errors = OFF
set rssi_scale = 100
set rssi_offset = 0
set rssi_invert = OFF
set rc_interp = AUTO
set rc_interp_ch = RPYT
set rc_interp_int = 19
set rc_smoothing_type = FILTER
set rc_smoothing_input_hz = 0
set rc_smoothing_derivative_hz = 0
set rc_smoothing_debug_axis = ROLL
set rc_smoothing_input_type = BIQUAD
set rc_smoothing_derivative_type = BIQUAD
set fpv_mix_degrees = 25
set max_aux_channels = 14
set serialrx_provider = SBUS
set serialrx_inverted = OFF
set spektrum_sat_bind = 0
set spektrum_sat_bind_autoreset = ON
set airmode_start_throttle_percent = 32
set rx_min_usec = 885
set rx_max_usec = 2115
set serialrx_halfduplex = OFF
set adc_device = 1
set input_filtering_mode = OFF
set blackbox_p_ratio = 32
set blackbox_device = SERIAL
set blackbox_record_acc = ON
set blackbox_mode = NORMAL
set min_throttle = 1070
set max_throttle = 2000
set min_command = 1000
set dshot_idle_value = 2000
set dshot_burst = OFF
set use_unsynced_pwm = OFF
set motor_pwm_protocol = DSHOT600
set motor_pwm_rate = 480
set motor_pwm_inversion = OFF
set motor_poles = 14
set thr_corr_value = 0
set thr_corr_angle = 800
set failsafe_delay = 200
set failsafe_off_delay = 10
set failsafe_throttle = 1350
set failsafe_switch_mode = STAGE1
set failsafe_throttle_low_delay = 200
set failsafe_procedure = AUTO-LAND
set align_board_roll = 0
```



```
set align_board_pitch = 0
set align_board_yaw = 0
set gimbal_mode = NORMAL
set bat_capacity = 1550
set vbat_max_cell_voltage = 42
set vbat_full_cell_voltage = 41
set vbat_min_cell_voltage = 37
set vbat_warning_cell_voltage = 35
set vbat_hysteresis = 1
set current_meter = ADC
set battery_meter = ADC
set vbat_detect_cell_voltage = 30
set use_vbat_alerts = ON
set use_cbat_alerts = OFF
set cbat_alert_percent = 10
set vbat_cutoff_percent = 100
set vbat_scale = 110
set vbat_divider = 10
set vbat_multiplier = 1
set ibata_scale = 400
set ibata_offset = 0
set ibatv_scale = 0
set ibatv_offset = 0
set beeper_inversion = ON
set beeper_od = OFF
set beeper_frequency = 0
set beeper_dshot_beacon_tone = 1
set yaw_motors_reversed = OFF
set crashflip_motor_percent = 0
set 3d_deadband_low = 1406
set 3d_deadband_high = 1514
set 3d_neutral = 1460
set 3d_deadband_throttle = 50
set 3d_limit_low = 1000
set 3d_limit_high = 2000
set 3d_switched_mode = OFF
set servo_center_pulse = 1500
set servo_pwm_rate = 50
set servo_lowpass_hz = 0
set tri_unarmed_servo = ON
set channel_forwarding_start = 4
set reboot_character = 82
set serial_update_rate_hz = 100
set accxy_deadband = 40
set accz_deadband = 40
set acc_unarmedcal = ON
set imu_dcm_kp = 2500
set imu_dcm_ki = 0
set small_angle = 180
set auto_disarm_delay = 5
set gyro_cal_on_first_arm = OFF
set gps_provider = UBLOX
set gps_sbas_mode = EGNOS
set gps_auto_config = ON
set gps_auto_baud = ON
set gps_ublox_use_galileo = OFF
set gps_rescue_angle = 32
set gps_rescue_initial_alt = 50
set gps_rescue_descent_dist = 200
set gps_rescue_ground_speed = 2000
set gps_rescue_throttle_p = 150
set gps_rescue_throttle_i = 20
set gps_rescue_throttle_d = 50
set gps_rescue_velocity_p = 80
```

```
set gps_rescue_velocity_i = 20
set gps_rescue_velocity_d = 15
set gps_rescue_yaw_p = 40
set gps_rescue_throttle_min = 1200
set gps_rescue_throttle_max = 1600
set gps_rescue_throttle_hover = 1280
set gps_rescue_sanity_checks = RESCUE_SANITY_OFF
set gps_rescue_min_sats = 8
set deadband = 0
set yaw_deadband = 0
set yaw_control_reversed = OFF
set pid_process_denom = 2
set runaway_takeoff_prevention = ON
set runaway_takeoff_deactivate_delay = 500
set runaway_takeoff_deactivate_throttle_percent = 25
set tlm_inverted = ON
set tlm_halfduplex = OFF
set frsky_default_lat = 0
set frsky_default_long = 0
set frsky_gps_format = 0
set frsky_unit = IMPERIAL
set frsky_vfas_precision = 0
set hott_alarm_int = 5
set pid_in_tlm = OFF
set report_cell_voltage = OFF
set ibus_sensor = 1,2,3,0,0,0,0,0,0,0,0,0,0,0,0
set smartport_use_extra_sensors = OFF
set ledstrip_visual_beeper = OFF
set ledstrip_grb_rgb = GRB
set osd_units = METRIC
set osd_warn_arwing_disable = ON
set osd_warn_batt_not_full = ON
set osd_warn_batt_warning = ON
set osd_warn_batt_critical = ON
set osd_warn_visual_beeper = ON
set osd_warn_crash_flip = ON
set osd_warn_esc_fail = ON
set osd_warn_core_temp = ON
set osd_rssi_alarm = 20
set osd_cap_alarm = 2200
set osd_alt_alarm = 500
set osd_esc_temp_alarm = -128
set osd_esc_rpm_alarm = -1
set osd_esc_current_alarm = -1
set osd_core_temp_alarm = 70
set osd_ah_max_pitch = 20
set osd_ah_max_roll = 40
set osd_tim1 = 2560
set osd_tim2 = 2561
set osd_vbat_pos = 2166
set osd_rssi_pos = 184
set osd_tim1_pos = 2551
set osd_tim2_pos = 2519
set osd_remaining_time_estimate_pos = 449
set osd_flymode_pos = 2541
set osd_anti_gravity_pos = 234
set osd_g_force_pos = 234
set osd_throttle_pos = 234
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_craft_name_pos = 234
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_pid_roll_pos = 234
set osd_pid_pitch_pos = 234
set osd_pid_yaw_pos = 234
set osd_debug_pos = 234
set osd_power_pos = 2178
set osd_pidrate_profile_pos = 234
set osd_warnings_pos = 2345
set osd_avg_cell_voltage_pos = 234
set osd_pit_ang_pos = 234
set osd_rol_ang_pos = 234
set osd_battery_usage_pos = 480
set osd_disarmed_pos = 395
set osd_nheading_pos = 234
set osd_nvario_pos = 216
set osd_esc_tmp_pos = 234
set osd_esc_rpm_pos = 234
set osd_rtc_date_time_pos = 418
set osd_adjustment_range_pos = 234
set osd_core_temp_pos = 234
set osd_stat_rtc_date_time = ON
set osd_stat_tim_1 = OFF
set osd_stat_tim_2 = ON
set osd_stat_max_spd = ON
set osd_stat_max_dist = ON
set osd_stat_min_batt = ON
set osd_stat_endbatt = OFF
set osd_stat_battery = OFF
set osd_stat_min_rssi = ON
set osd_stat_max_curr = ON
set osd_stat_used_mah = ON
set osd_stat_max_alt = ON
set osd_stat_bbox = ON
set osd_stat_bb_no = ON
set task_statistics = ON
set debug_mode = NONE
set rate_6pos_switch = OFF
set cpu overclock = OFF
set pwr_on_arm_grace = 5
set vtx_band = 4
set vtx_channel = 1
set vtx_power = 1
set vtx_low_power_disarm = OFF
set vtx_freq = 5740
set vtx_pit_mode_freq = 0
set vtx_halfduplex = ON
set vcd_video_system = AUTO
set vcd_h_offset = 0
set vcd_v_offset = 0
set max7456_clock = DEFAULT
set max7456_spi_bus = 3
set displayport_msp_col_adjust = 0
set displayport_msp_row_adjust = 0
set displayport_max7456_col_adjust = 0
set displayport_max7456_row_adjust = 0
set displayport_max7456_inv = OFF
```

```
set displayport_max7456_blk = 0
set displayport_max7456_wht = 2
set esc_sensor_halfduplex = OFF
set esc_sensor_current_offset = 0
set led_inversion = 0
set dashboard_i2c_bus = 1
set dashboard_i2c_addr = 60
set camera_control_mode = HARDWARE_PWM
set camera_control_ref_voltage = 330
set camera_control_key_delay = 180
set camera_control_internal_resistance = 470
set camera_control_inverted = OFF
set pinio_config = 1,1,1,1
set pinio_box = 255,255,255,255
set usb_hid_cdc = OFF
set usb_msc_pin_pullup = OFF
set flash_spi_bus = 3
set rcdevice_init_dev_attempts = 4
set rcdevice_init_dev_attempt_interval = 1000
```

```
# profile
profile 0
```

```
set dterm_lowpass_type = PT1
set dterm_lowpass_hz = 100
set dterm_lowpass2_hz = 200
set dterm_notch_hz = 0
set dterm_notch_cutoff = 0
set vbat_pid_gain = ON
set pid_at_min_throttle = ON
set anti_gravity_mode = SMOOTH
set anti_gravity_threshold = 350
set anti_gravity_gain = 5000
set feedforward_transition = 0
set acc_limit_yaw = 100
set acc_limit = 0
set crash_dthreshold = 50
set crash_gthreshold = 400
set crash_setpoint_threshold = 350
set crash_time = 500
set crash_delay = 0
set crash_recovery_angle = 10
set crash_recovery_rate = 100
set crash_limit_yaw = 200
set crash_recovery = OFF
set iterm_rotation = OFF
set smart_feedforward = OFF
set iterm_relax = RP
set iterm_relax_type = SETPOINT
set iterm_relax_cutoff = 9
set iterm_windup = 40
set iterm_limit = 150
set pidsum_limit = 500
set pidsum_limit_yaw = 400
set yaw_lowpass_hz = 0
set throttle_boost = 10
set throttle_boost_cutoff = 15
set acro_trainer_angle_limit = 20
set acro_trainer_lookahead_ms = 50
set acro_trainer_debug_axis = ROLL
set acro_trainer_gain = 75
set p_pitch = 50
set i_pitch = 50
set d_pitch = 27
```

```
set f_pitch = 100
set p_roll = 46
set i_roll = 45
set d_roll = 25
set f_roll = 100
set p_yaw = 40
set i_yaw = 120
set d_yaw = 0
set f_yaw = 100
set p_level = 50
set i_level = 50
set d_level = 75
set level_limit = 55
set horizon_tilt_effect = 75
set horizon_tilt_expert_mode = OFF
set abs_control_gain = 10
set abs_control_limit = 90
set abs_control_error_limit = 20
```

```
# rateprofile
rateprofile 0
```

```
set thr_mid = 50
set thr_expo = 0
set rates_type = BETAFLIGHT
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
set yaw_srate = 70
set tpa_rate = 10
set tpa_breakpoint = 1650
set throttle_limit_type = OFF
set throttle_limit_percent = 100
```