

**# DUMP**  
**# version**  
**# Betaflight / STM32F411 (S411) 4.4.1 Apr 6 2023 / 04:23:14 (e43d591) MSP API: 1.45**  
**# config: YES**  
**# start the command batch**  
**batch start**  
**board\_name FLYWOOF411\_5IN1\_AIO**  
**manufacturer\_id FLWO**  
**# name: FLYWOO**  
**# resources**  
**resource BEEPER 1 C14**  
**resource MOTOR 1 B10**  
**resource MOTOR 2 A08**  
**resource MOTOR 3 B07**  
**resource MOTOR 4 B06**  
**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 A02**  
**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 SERIAL\_TX 1 A09**  
**resource SERIAL\_TX 2 A02**  
**resource SERIAL\_TX 3 NONE**  
**resource SERIAL\_TX 4 NONE**  
**resource SERIAL\_TX 5 NONE**  
**resource SERIAL\_TX 6 NONE**  
**resource SERIAL\_TX 7 NONE**  
**resource SERIAL\_TX 8 NONE**  
**resource SERIAL\_TX 9 NONE**  
**resource SERIAL\_TX 10 NONE**  
**resource SERIAL\_TX 11 B00**  
**resource SERIAL\_TX 12 NONE**

resource SERIAL\_RX 1 A10  
resource SERIAL\_RX 2 A03  
resource SERIAL\_RX 3 NONE  
resource SERIAL\_RX 4 NONE  
resource SERIAL\_RX 5 NONE  
resource SERIAL\_RX 6 NONE  
resource SERIAL\_RX 7 NONE  
resource SERIAL\_RX 8 NONE  
resource SERIAL\_RX 9 NONE  
resource SERIAL\_RX 10 NONE  
resource SERIAL\_RX 11 B04  
resource SERIAL\_RX 12 NONE  
resource INVERTER 1 NONE  
resource INVERTER 2 NONE  
resource INVERTER 3 NONE  
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 INVERTER 12 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 C13  
resource LED 2 NONE  
resource LED 3 NONE  
resource RX\_BIND 1 NONE  
resource RX\_BIND\_PLUG 1 NONE  
resource SPI\_SCK 1 A05  
resource SPI\_SCK 2 B13  
resource SPI\_SCK 3 B03  
resource SPI\_MISO 1 A06  
resource SPI\_MISO 2 B14  
resource SPI\_MISO 3 NONE  
resource SPI\_MOSI 1 A07  
resource SPI\_MOSI 2 B15  
resource SPI\_MOSI 3 B05  
resource ESCSERIAL 1 NONE  
resource ADC\_BATT 1 B01  
resource ADC\_RSSI 1 NONE  
resource ADC\_CURR 1 A01

resource ADC\_EXT 1 NONE  
resource BARO\_CS 1 NONE  
resource BARO\_EOC 1 NONE  
resource BARO\_XCLR 1 NONE  
resource COMPASS\_CS 1 NONE  
resource COMPASS\_EXTI 1 NONE  
resource SDCARD\_CS 1 NONE  
resource SDCARD\_DETECT 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 NONE  
resource OSD\_CS 1 B12  
resource RX\_SPI\_CS 1 NONE  
resource RX\_SPI\_EXTI 1 NONE  
resource RX\_SPI\_BIND 1 NONE  
resource RX\_SPI\_LED 1 NONE  
resource RX\_SPI\_CC2500\_TX\_EN 1 NONE  
resource RX\_SPI\_CC2500\_LNA\_EN 1 NONE  
resource RX\_SPI\_CC2500\_ANT\_SEL 1 NONE  
resource RX\_SPI\_EXPRESSLRS\_RESET 1 NONE  
resource RX\_SPI\_EXPRESSLRS\_BUSY 1 NONE  
resource GYRO\_EXTI 1 B02  
resource GYRO\_EXTI 2 NONE  
resource GYRO\_CS 1 A04  
resource GYRO\_CS 2 NONE  
resource USB\_DETECT 1 C15  
resource PULLUP 1 NONE  
resource PULLUP 2 NONE  
resource PULLUP 3 NONE  
resource PULLUP 4 NONE  
resource PULLDOWN 1 NONE  
resource PULLDOWN 2 NONE  
resource PULLDOWN 3 NONE  
resource PULLDOWN 4 NONE  
# timer  
timer A02 AF3  
# pin A02: TIM9 CH1 (AF3)  
timer A08 AF1  
# pin A08: TIM1 CH1 (AF1)  
timer B03 AF1  
# pin B03: TIM2 CH2 (AF1)  
timer B10 AF1  
# pin B10: TIM2 CH3 (AF1)  
timer A15 AF1  
# pin A15: TIM2 CH1 (AF1)

timer B06 AF2  
# pin B06: TIM4 CH1 (AF2)  
timer B07 AF2  
# pin B07: TIM4 CH2 (AF2)  
timer B00 AF2  
# pin B00: TIM3 CH3 (AF2)  
timer B04 AF2  
# pin B04: TIM3 CH1 (AF2)  
timer A00 AF2  
# pin A00: TIM5 CH1 (AF2)  
# dma  
dma SPI\_MOSI 1 NONE  
dma SPI\_MOSI 2 NONE  
dma SPI\_MOSI 3 NONE  
dma SPI\_MISO 1 NONE  
dma SPI\_MISO 2 NONE  
dma SPI\_MISO 3 NONE  
dma SPI\_TX 1 NONE  
dma SPI\_TX 2 NONE  
dma SPI\_TX 3 NONE  
dma SPI\_RX 1 NONE  
dma SPI\_RX 2 NONE  
dma SPI\_RX 3 NONE  
dma ADC 1 0  
# ADC 1: DMA2 Stream 0 Channel 0  
dma ADC 2 NONE  
dma ADC 3 NONE  
dma UART\_TX 1 NONE  
dma UART\_TX 2 NONE  
dma UART\_TX 3 NONE  
dma UART\_TX 4 NONE  
dma UART\_TX 5 NONE  
dma UART\_TX 6 NONE  
dma UART\_TX 7 NONE  
dma UART\_TX 8 NONE  
dma UART\_RX 1 NONE  
dma UART\_RX 2 NONE  
dma UART\_RX 3 NONE  
dma UART\_RX 4 NONE  
dma UART\_RX 5 NONE  
dma UART\_RX 6 NONE  
dma UART\_RX 7 NONE  
dma UART\_RX 8 NONE  
dma pin A02 NONE  
dma pin A08 1  
# pin A08: DMA2 Stream 1 Channel 6  
dma pin B03 0  
# pin B03: DMA1 Stream 6 Channel 3

**dma pin B10 0**  
**# pin B10: DMA1 Stream 1 Channel 3**  
**dma pin A15 0**  
**# pin A15: DMA1 Stream 5 Channel 3**  
**dma pin B06 0**  
**# pin B06: DMA1 Stream 0 Channel 2**  
**dma pin B07 0**  
**# pin B07: DMA1 Stream 3 Channel 2**  
**dma pin B00 0**  
**# pin B00: DMA1 Stream 7 Channel 5**  
**dma pin B04 0**  
**# pin B04: DMA1 Stream 4 Channel 5**  
**dma pin A00 0**  
**# pin A00: DMA1 Stream 2 Channel 6**  
**# 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 -ESC\_SENSOR**  
**feature -ANTI\_GRAVITY**  
**feature RX\_SERIAL**  
**feature SOFTSERIAL**  
**feature OSD**  
**feature AIRMODE**  
**feature ANTI\_GRAVITY**  
**# serial**  
**serial 20 1 115200 57600 0 115200**  
**serial 0 64 115200 57600 0 115200**  
**serial 1 131073 115200 57600 0 115200**  
**serial 30 0 115200 57600 0 115200**  
**# 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 mixer
smix reset
# beeper
beeper GYRO_CALIBRATED
beeper RX_LOST
beeper RX_LOST_LANDING
beeper DISARMING
beeper ARMING
beeper ARMING_GPS_FIX
beeper ARMING_GPS_NO_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_CLOSE
beeper RC_SMOOTHING_INIT_FAIL
# beacon
beacon -RX_LOST
beacon -RX_SET
# map
map AETR1234
# aux
aux 0 0 2 1350 2100 0 0
aux 1 2 2 1700 2100 0 0
aux 2 0 0 900 900 0 0
aux 3 0 0 900 900 0 0
```

aux 4 0 0 900 900 0 0  
aux 5 0 0 900 900 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  
adjrange 15 0 0 900 900 0 0 0 0  
adjrange 16 0 0 900 900 0 0 0 0  
adjrange 17 0 0 900 900 0 0 0 0  
adjrange 18 0 0 900 900 0 0 0 0  
adjrange 19 0 0 900 900 0 0 0 0  
adjrange 20 0 0 900 900 0 0 0 0  
adjrange 21 0 0 900 900 0 0 0 0  
adjrange 22 0 0 900 900 0 0 0 0  
adjrange 23 0 0 900 900 0 0 0 0  
adjrange 24 0 0 900 900 0 0 0 0  
adjrange 25 0 0 900 900 0 0 0 0  
adjrange 26 0 0 900 900 0 0 0 0  
adjrange 27 0 0 900 900 0 0 0 0  
adjrange 28 0 0 900 900 0 0 0 0  
adjrange 29 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**  
**# vtxtable**  
**vtxtable bands 5**  
**vtxtable channels 8**  
**vtxtable band 1 BOSCAM\_A A CUSTOM 5865 5845 5825 5805 5785 5765 5745 5725**  
**vtxtable band 2 BOSCAM\_B B CUSTOM 5733 5752 5771 5790 5809 5828 5847 5866**  
**vtxtable band 3 BOSCAM\_E E CUSTOM 5705 5685 5665 5645 5885 5905 5925 5945**  
**vtxtable band 4 FATSHARK F CUSTOM 5740 5760 5780 5800 5820 5840 5860 5880**  
**vtxtable band 5 RACEBAND R CUSTOM 5658 5695 5732 5769 5806 5843 5880 5917**  
**vtxtable powerlevels 5**  
**vtxtable powervalues 25 100 200 400 600**  
**vtxtable powerlabels 25 50 100 150 200**  
**# vtx**  
**vtx 0 0 0 0 0 900 900**  
**vtx 1 0 0 0 0 900 900**  
**vtx 2 0 0 0 0 900 900**  
**vtx 3 0 0 0 0 900 900**  
**vtx 4 0 0 0 0 900 900**  
**vtx 5 0 0 0 0 900 900**  
**vtx 6 0 0 0 0 900 900**  
**vtx 7 0 0 0 0 900 900**  
**vtx 8 0 0 0 0 900 900**  
**vtx 9 0 0 0 0 900 900**  
**# rxfail**  
**rxfail 0 a**  
**rxfail 1 a**  
**rxfail 2 a**  
**rxfail 3 a**  
**rxfail 4 h**  
**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 gyro\_hardware\_lpf = NORMAL**  
**set gyro\_lpf1\_type = PT1**



set gyro\_lpf1\_static\_hz = 0  
set gyro\_lpf2\_type = PT1  
set gyro\_lpf2\_static\_hz = 525  
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 = AUTO  
set yaw\_spin\_threshold = 1950  
set gyro\_to\_use = FIRST  
set dyn\_notch\_count = 0  
set dyn\_notch\_q = 300  
set dyn\_notch\_min\_hz = 100  
set dyn\_notch\_max\_hz = 600  
set gyro\_lpf1\_dyn\_min\_hz = 262  
set gyro\_lpf1\_dyn\_max\_hz = 525  
set gyro\_lpf1\_dyn\_expo = 5  
set gyro\_filter\_debug\_axis = ROLL  
set acc\_hardware = AUTO  
set acc\_lpf\_hz = 25  
set acc\_trim\_pitch = 0  
set acc\_trim\_roll = 0  
set acc\_calibration = -113,40,6,1  
set align\_mag = DEFAULT  
set mag\_align\_roll = 0  
set mag\_align\_pitch = 0  
set mag\_align\_yaw = 0  
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\_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 = NONE  
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 rssi\_src\_frame\_lpf\_period = 30  
set rssi\_smoothing = 125  
set rc\_smoothing = ON  
set rc\_smoothing\_auto\_factor = 30  
set rc\_smoothing\_auto\_factor\_throttle = 30  
set rc\_smoothing\_setpoint\_cutoff = 0  
set rc\_smoothing\_feedforward\_cutoff = 0  
set rc\_smoothing\_throttle\_cutoff = 0  
set rc\_smoothing\_debug\_axis = ROLL  
set fpv\_mix\_degrees = 0  
set max\_aux\_channels = 14  
set serialrx\_provider = CRSF  
set serialrx\_inverted = OFF  
set spektrum\_sat\_bind = 0  
set spektrum\_sat\_bind\_autoreset = ON  
set srxl2\_unit\_id = 1  
set srxl2\_baud\_fast = ON  
set sbus\_baud\_fast = OFF  
set crsf\_use\_negotiated\_baud = OFF  
set airmode\_start\_throttle\_percent = 25  
set rx\_min\_usec = 885  
set rx\_max\_usec = 2115  
set serialrx\_halfduplex = OFF  
set msp\_override\_channels\_mask = 0  
set rx\_spi\_protocol = FRSKY\_D  
set rx\_spi\_bus = 3  
set rx\_spi\_led\_inversion = OFF  
set adc\_device = 1  
set adc\_vrefint\_calibration = 0  
set adc\_tempsensor\_calibration30 = 0  
set adc\_tempsensor\_calibration110 = 0  
set input\_filtering\_mode = OFF  
set blackbox\_sample\_rate = 1/4  
set blackbox\_device = SPIFLASH  
set blackbox\_disable\_pids = OFF  
set blackbox\_disable\_rc = OFF  
set blackbox\_disable\_setpoint = OFF  
set blackbox\_disable\_bat = OFF  
set blackbox\_disable\_mag = OFF  
set blackbox\_disable\_alt = OFF  
set blackbox\_disable\_rssi = OFF  
set blackbox\_disable\_gyro = OFF  
set blackbox\_disable\_acc = OFF  
set blackbox\_disable\_debug = OFF  
set blackbox\_disable\_motors = OFF  
set blackbox\_mode = NORMAL

**set blackbox\_high\_resolution = OFF**  
**set min\_throttle = 1070**  
**set max\_throttle = 2000**  
**set min\_command = 1000**  
**set dshot\_idle\_value = 2000**  
**set dshot\_burst = ON**  
**set dshot\_bidir = ON**  
**set dshot\_edt = OFF**  
**set dshot\_bitbang = AUTO**  
**set dshot\_bitbang\_timer = AUTO**  
**set use\_unsynced\_pwm = OFF**  
**set motor\_pwm\_protocol = DSHOT300**  
**set motor\_pwm\_rate = 480**  
**set motor\_pwm\_inversion = OFF**  
**set motor\_poles = 12**  
**set motor\_output\_reordering = 0,1,2,3,4,5,6,7**  
**set thr\_corr\_value = 0**  
**set thr\_corr\_angle = 800**  
**set failsafe\_delay = 15**  
**set failsafe\_off\_delay = 10**  
**set failsafe\_throttle = 1000**  
**set failsafe\_switch\_mode = STAGE1**  
**set failsafe\_throttle\_low\_delay = 100**  
**set failsafe\_procedure = DROP**  
**set failsafe\_recovery\_delay = 10**  
**set failsafe\_stick\_threshold = 30**  
**set align\_board\_roll = 0**  
**set align\_board\_pitch = 0**  
**set align\_board\_yaw = 0**  
**set gimbal\_mode = NORMAL**  
**set bat\_capacity = 0**  
**set vbat\_max\_cell\_voltage = 440**  
**set vbat\_full\_cell\_voltage = 410**  
**set vbat\_min\_cell\_voltage = 330**  
**set vbat\_warning\_cell\_voltage = 330**  
**set vbat\_hysteresis = 1**  
**set current\_meter = ADC**  
**set battery\_meter = ADC**  
**set vbat\_detect\_cell\_voltage = 300**  
**set use\_vbat\_alerts = ON**  
**set use\_cbat\_alerts = OFF**  
**set cbat\_alert\_percent = 10**  
**set vbat\_cutoff\_percent = 100**  
**set force\_battery\_cell\_count = 0**  
**set vbat\_display\_lpf\_period = 30**  
**set vbat\_sag\_lpf\_period = 2**  
**set ibat\_lpf\_period = 10**  
**set vbat\_duration\_for\_warning = 0**

set vbat\_duration\_for\_critical = 0  
set vbat\_scale = 110  
set vbat\_divider = 10  
set vbat\_multiplier = 1  
set ibata\_scale = 200  
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 = ON  
set mixer\_type = LEGACY  
set crashflip\_motor\_percent = 0  
set crashflip\_expo = 35  
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 imu\_dcm\_kp = 2500  
set imu\_dcm\_ki = 0  
set small\_angle = 25  
set imu\_process\_denom = 2  
set auto\_disarm\_delay = 5  
set gyro\_cal\_on\_first\_arm = OFF  
set deadband = 0  
set yaw\_deadband = 0  
set yaw\_control\_reversed = OFF  
set pid\_process\_denom = 4  
set runaway\_takeoff\_prevention = ON  
set runaway\_takeoff\_deactivate\_delay = 500  
set runaway\_takeoff\_deactivate\_throttle\_percent = 20  
set simplified\_gyro\_filter = ON  
set simplified\_gyro\_filter\_multiplier = 105  
set tlm\_inverted = OFF  
set tlm\_halfduplex = ON  
set frsky\_vfas\_precision = 0

set hott\_alarm\_int = 5  
set pid\_in\_tlm = OFF  
set report\_cell\_voltage = OFF  
set telemetry\_disabled\_voltage = OFF  
set telemetry\_disabled\_current = OFF  
set telemetry\_disabled\_fuel = OFF  
set telemetry\_disabled\_mode = OFF  
set telemetry\_disabled\_acc\_x = OFF  
set telemetry\_disabled\_acc\_y = OFF  
set telemetry\_disabled\_acc\_z = OFF  
set telemetry\_disabled\_pitch = OFF  
set telemetry\_disabled\_roll = OFF  
set telemetry\_disabled\_heading = OFF  
set telemetry\_disabled\_altitude = OFF  
set telemetry\_disabled\_vario = OFF  
set telemetry\_disabled\_lat\_long = OFF  
set telemetry\_disabled\_ground\_speed = OFF  
set telemetry\_disabled\_distance = OFF  
set telemetry\_disabled\_esc\_current = ON  
set telemetry\_disabled\_esc\_voltage = ON  
set telemetry\_disabled\_esc\_rpm = ON  
set telemetry\_disabled\_esc\_temperature = ON  
set telemetry\_disabled\_temperature = OFF  
set telemetry\_disabled\_cap\_used = ON  
set sdcard\_detect\_inverted = OFF  
set sdcard\_mode = OFF  
set sdcard\_spi\_bus = 0  
set sdio\_clk\_bypass = OFF  
set sdio\_use\_cache = OFF  
set sdio\_use\_4bit\_width = OFF  
set osd\_units = METRIC  
set osd\_warn\_bitmask = 8191  
set osd\_rssi\_alarm = 20  
set osd\_link\_quality\_alarm = 80  
set osd\_rssi\_dbm\_alarm = -60  
set osd\_rsnr\_alarm = 4  
set osd\_cap\_alarm = 2200  
set osd\_alt\_alarm = 100  
set osd\_distance\_alarm = 0  
set osd\_esc\_temp\_alarm = 0  
set osd\_esc\_rpm\_alarm = -1  
set osd\_esc\_current\_alarm = -1  
set osd\_core\_temp\_alarm = 70  
set osd\_ah\_max\_pit = 20  
set osd\_ah\_max\_rol = 40  
set osd\_ah\_invert = OFF  
set osd\_logo\_on\_arming = OFF  
set osd\_logo\_on\_arming\_duration = 5

set osd\_tim1 = 2560  
set osd\_tim2 = 2561  
set osd\_vbat\_pos = 2307  
set osd\_rssi\_pos = 195  
set osd\_link\_quality\_pos = 2211  
set osd\_link\_tx\_power\_pos = 234  
set osd\_rssi\_dbm\_pos = 163  
set osd\_rsnr\_pos = 234  
set osd\_tim\_1\_pos = 2390  
set osd\_tim\_2\_pos = 2422  
set osd\_remaining\_time\_estimate\_pos = 234  
set osd\_flymode\_pos = 2294  
set osd\_anti\_gravity\_pos = 234  
set osd\_g\_force\_pos = 234  
set osd\_throttle\_pos = 2326  
set osd\_vtx\_channel\_pos = 234  
set osd\_crosshairs\_pos = 205  
set osd\_ah\_sbar\_pos = 206  
set osd\_ah\_pos = 78  
set osd\_current\_pos = 2370  
set osd\_mah\_drawn\_pos = 2402  
set osd\_wh\_drawn\_pos = 234  
set osd\_motor\_diag\_pos = 234  
set osd\_craft\_name\_pos = 2083  
set osd\_pilot\_name\_pos = 234  
set osd\_gps\_speed\_pos = 234  
set osd\_gps\_lon\_pos = 234  
set osd\_gps\_lat\_pos = 234  
set osd\_gps\_sats\_pos = 234  
set osd\_home\_dir\_pos = 234  
set osd\_home\_dist\_pos = 234  
set osd\_flight\_dist\_pos = 234  
set osd\_compass\_bar\_pos = 234  
set osd\_altitude\_pos = 234  
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 = 234  
set osd\_pidrate\_profile\_pos = 234  
set osd\_warnings\_pos = 2442  
set osd\_avg\_cell\_voltage\_pos = 2339  
set osd\_pit\_ang\_pos = 234  
set osd\_rol\_ang\_pos = 234  
set osd\_battery\_usage\_pos = 234  
set osd\_disarmed\_pos = 2411  
set osd\_nheading\_pos = 234  
set osd\_up\_down\_reference\_pos = 205

set osd\_ready\_mode\_pos = 234  
set osd\_esc\_tmp\_pos = 234  
set osd\_esc\_rpm\_pos = 234  
set osd\_esc\_rpm\_freq\_pos = 234  
set osd\_rtc\_date\_time\_pos = 234  
set osd\_adjustment\_range\_pos = 234  
set osd\_flip\_arrow\_pos = 234  
set osd\_core\_temp\_pos = 234  
set osd\_log\_status\_pos = 234  
set osd\_stick\_overlay\_left\_pos = 234  
set osd\_stick\_overlay\_right\_pos = 234  
set osd\_stick\_overlay\_radio\_mode = 2  
set osd\_rate\_profile\_name\_pos = 234  
set osd\_pid\_profile\_name\_pos = 234  
set osd\_profile\_name\_pos = 234  
set osd\_rcchannels\_pos = 234  
set osd\_camera\_frame\_pos = 35  
set osd\_efficiency\_pos = 234  
set osd\_total\_flights\_pos = 234  
set osd\_aux\_pos = 234  
set osd\_sys\_goggle\_voltage\_pos = 234  
set osd\_sys\_vtx\_voltage\_pos = 234  
set osd\_sys\_bitrate\_pos = 234  
set osd\_sys\_delay\_pos = 234  
set osd\_sys\_distance\_pos = 234  
set osd\_sys\_lq\_pos = 234  
set osd\_sys\_goggle\_dvr\_pos = 234  
set osd\_sys\_vtx\_dvr\_pos = 234  
set osd\_sys\_warnings\_pos = 234  
set osd\_sys\_vtx\_temp\_pos = 234  
set osd\_sys\_fan\_speed\_pos = 234  
set osd\_stat\_bitmask = 14124  
set osd\_profile = 1  
set osd\_profile\_1\_name = -  
set osd\_profile\_2\_name = -  
set osd\_profile\_3\_name = -  
set osd\_gps\_sats\_show\_hdop = OFF  
set osd\_displayport\_device = MSP  
set osd\_rcchannels = -1,-1,-1,-1  
set osd\_camera\_frame\_width = 24  
set osd\_camera\_frame\_height = 11  
set osd\_stat\_avg\_cell\_value = OFF  
set osd\_framerate\_hz = 12  
set osd\_menu\_background = TRANSPARENT  
set osd\_aux\_channel = 1  
set osd\_aux\_scale = 200  
set osd\_aux\_symbol = 65  
set osd\_canvas\_width = 30





set rcdevice\_init\_dev\_attempts = 6  
set rcdevice\_init\_dev\_attempt\_interval = 1000  
set rcdevice\_protocol\_version = 0  
set rcdevice\_feature = 0  
set gyro\_1\_bustype = SPI  
set gyro\_1\_spibus = 1  
set gyro\_1\_i2cBus = 0  
set gyro\_1\_i2c\_address = 0  
set gyro\_1\_sensor\_align = CW0FLIP  
set gyro\_1\_align\_roll = 0  
set gyro\_1\_align\_pitch = 1800  
set gyro\_1\_align\_yaw = 0  
set gyro\_2\_bustype = SPI  
set gyro\_2\_spibus = 0  
set gyro\_2\_i2cBus = 0  
set gyro\_2\_i2c\_address = 0  
set gyro\_2\_sensor\_align = CW0  
set gyro\_2\_align\_roll = 0  
set gyro\_2\_align\_pitch = 0  
set gyro\_2\_align\_yaw = 0  
set i2c1\_pullup = OFF  
set i2c1\_clockspeed\_khz = 800  
set i2c2\_pullup = OFF  
set i2c2\_clockspeed\_khz = 800  
set i2c3\_pullup = OFF  
set i2c3\_clockspeed\_khz = 800  
set mco2\_on\_pc9 = OFF  
set spektrum\_spi\_protocol = 0  
set spektrum\_spi\_mfg\_id = 0,0,0,0  
set spektrum\_spi\_num\_channels = 0  
set expresslrs\_uid = 0,0,0,0,0,0  
set expresslrs\_domain = AU433  
set expresslrs\_rate\_index = 0  
set expresslrs\_switch\_mode = WIDE  
set expresslrs\_model\_id = 255  
set scheduler\_relax\_rx = 1  
set scheduler\_relax\_osd = 1  
set serialmsp\_halfduplex = OFF  
set timezone\_offset\_minutes = 0  
set rpm\_filter\_harmonics = 3  
set rpm\_filter\_q = 500  
set rpm\_filter\_min\_hz = 100  
set rpm\_filter\_fade\_range\_hz = 50  
set rpm\_filter\_lpf\_hz = 150  
set flysky\_spi\_tx\_id = 0  
set flysky\_spi\_rf\_channels = 0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0  
set stats\_min\_armed\_time\_s = -1  
set stats\_total\_flights = 0

```
set stats_total_time_s = 0
set stats_total_dist_m = 0
set craft_name = FLYWOO
set pilot_name = -
set altitude_source = DEFAULT
set altitude_prefer_baro = 100
set altitude_lpf = 300
set altitude_d_lpf = 100
set box_user_1_name = -
set box_user_2_name = -
set box_user_3_name = -
set box_user_4_name = -
profile 0
# profile 0
set profile_name = -
set dterm_lpf1_dyn_min_hz = 63
set dterm_lpf1_dyn_max_hz = 127
set dterm_lpf1_dyn_expo = 5
set dterm_lpf1_type = PT1
set dterm_lpf1_static_hz = 0
set dterm_lpf2_type = PT1
set dterm_lpf2_static_hz = 127
set dterm_notch_hz = 0
set dterm_notch_cutoff = 0
set vbat_sag_compensation = 100
set pid_at_min_throttle = ON
set anti_gravity_gain = 80
set anti_gravity_cutoff_hz = 5
set anti_gravity_p_gain = 100
set acc_limit_yaw = 0
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 iterm_relax = RP
set iterm_relax_type = SETPOINT
set iterm_relax_cutoff = 25
set iterm_windup = 85
set iterm_limit = 400
set pidsum_limit = 500
set pidsum_limit_yaw = 400
```

**set yaw\_lowpass\_hz = 100**  
**set throttle\_boost = 5**  
**set throttle\_boost\_cutoff = 15**  
**set p\_pitch = 74**  
**set i\_pitch = 133**  
**set d\_pitch = 45**  
**set f\_pitch = 151**  
**set p\_roll = 71**  
**set i\_roll = 127**  
**set d\_roll = 44**  
**set f\_roll = 145**  
**set p\_yaw = 71**  
**set i\_yaw = 127**  
**set d\_yaw = 0**  
**set f\_yaw = 145**  
**set angle\_level\_strength = 50**  
**set horizon\_level\_strength = 50**  
**set horizon\_transition = 75**  
**set level\_limit = 55**  
**set horizon\_tilt\_effect = 75**  
**set horizon\_tilt\_expert\_mode = OFF**  
**set abs\_control\_gain = 0**  
**set abs\_control\_limit = 90**  
**set abs\_control\_error\_limit = 20**  
**set abs\_control\_cutoff = 11**  
**set use\_integrated\_yaw = OFF**  
**set integrated\_yaw\_relax = 200**  
**set d\_min\_roll = 41**  
**set d\_min\_pitch = 42**  
**set d\_min\_yaw = 0**  
**set d\_max\_gain = 37**  
**set d\_max\_advance = 0**  
**set motor\_output\_limit = 100**  
**set auto\_profile\_cell\_count = 0**  
**set launch\_control\_mode = NORMAL**  
**set launch\_trigger\_allow\_reset = ON**  
**set launch\_trigger\_throttle\_percent = 20**  
**set launch\_angle\_limit = 0**  
**set launch\_control\_gain = 40**  
**set thrust\_linear = 30**  
**set transient\_throttle\_limit = 0**  
**set feedforward\_transition = 0**  
**set feedforward\_averaging = OFF**  
**set feedforward\_smooth\_factor = 25**  
**set feedforward\_jitter\_factor = 5**  
**set feedforward\_boost = 15**  
**set feedforward\_max\_rate\_limit = 90**  
**set dyn\_idle\_min\_rpm = 0**

```
set dyn_idle_p_gain = 50
set dyn_idle_i_gain = 50
set dyn_idle_d_gain = 50
set dyn_idle_max_increase = 150
set level_race_mode = OFF
set simplified_pids_mode = RPY
set simplified_master_multiplier = 110
set simplified_i_gain = 100
set simplified_d_gain = 125
set simplified_pi_gain = 145
set simplified_dmax_gain = 25
set simplified_feedforward_gain = 110
set simplified_pitch_d_gain = 90
set simplified_pitch_pi_gain = 100
set simplified_dterm_filter = ON
set simplified_dterm_filter_multiplier = 85
set tpa_mode = D
set tpa_rate = 65
set tpa_breakpoint = 1350
rateprofile 0
# rateprofile 0
set rateprofile_name = -
set thr_mid = 50
set thr_expo = 0
set rates_type = BETAFLIGHT
set quickrates_rc_expo = OFF
set roll_rc_rate = 108
set pitch_rc_rate = 108
set yaw_rc_rate = 100
set roll_expo = 0
set pitch_expo = 0
set yaw_expo = 0
set roll_srate = 73
set pitch_srate = 73
set yaw_srate = 70
set throttle_limit_type = OFF
set throttle_limit_percent = 100
set roll_rate_limit = 1998
set pitch_rate_limit = 1998
set yaw_rate_limit = 1998
set roll_level_expo = 0
set pitch_level_expo = 0
# end the command batch
batch end
SAVE
```