

```
#  
# DUMP  
###WARNING: NO CUSTOM DEFAULTS FOUND###  
# version  
# Betaflight / STM32F405 (S405) 4.3.1 Jul 13 2022 / 03:32:11 (8d4f005) MSP API: 1.44  
###ERROR IN dump: NO CONFIG FOUND###  
# start the command batch  
batch start  
board_name FLYWOOF405NANO  
manufacturer_id FLWO  
# name: -  
# resources  
resource BEEPER 1 C13  
resource MOTOR 1 B00  
resource MOTOR 2 B01  
resource MOTOR 3 A03  
resource MOTOR 4 A02  
resource MOTOR 5 B05  
resource MOTOR 6 C09  
resource MOTOR 7 B04  
resource MOTOR 8 C08  
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 B08  
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 SONAR_TRIGGER 1 NONE  
resource SONAR_ECHO 1 NONE  
resource LED_STRIP 1 A09  
resource SERIAL_TX 1 B06  
resource SERIAL_TX 2 D05  
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\_TX 12 NONE  
resource SERIAL\_RX 1 A10  
resource SERIAL\_RX 2 D06  
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 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 C14  
resource LED 2 NONE  
resource LED 3 NONE  
resource RX\_BIND 1 NONE  
resource RX\_BIND\_PLUG 1 NONE  
resource TRANSPONDER 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 B08  
resource CAMERA\_CONTROL 1 NONE  
resource ADC\_BATT 1 C03  
resource ADC\_RSSI 1 C00  
resource ADC\_CURR 1 C02  
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 B03  
resource OSD\_CS 1 B14  
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 B13  
resource GYRO\_EXTI 2 NONE  
resource GYRO\_CS 1 B12  
resource GYRO\_CS 2 NONE  
resource USB\_DETECT 1 A08  
resource VTX\_POWER 1 NONE  
resource VTX\_CS 1 NONE  
resource VTX\_DATA 1 NONE  
resource VTX\_CLK 1 NONE  
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 B00 AF2**  
**# pin B00: TIM3 CH3 (AF2)**  
**timer B01 AF2**  
**# pin B01: TIM3 CH4 (AF2)**  
**timer A03 AF1**  
**# pin A03: TIM2 CH4 (AF1)**  
**timer A02 AF1**  
**# pin A02: TIM2 CH3 (AF1)**  
**timer B05 AF2**  
**# pin B05: TIM3 CH2 (AF2)**  
**timer B07 AF2**  
**# pin B07: TIM4 CH2 (AF2)**  
**timer C09 AF3**  
**# pin C09: TIM8 CH4 (AF3)**  
**timer C08 AF3**  
**# pin C08: TIM8 CH3 (AF3)**  
**timer A09 AF1**  
**# pin A09: TIM1 CH2 (AF1)**  
**# 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 B00 0**  
**# pin B00: DMA1 Stream 7 Channel 5**  
**dma pin B01 0**  
**# pin B01: DMA1 Stream 2 Channel 5**  
**dma pin A03 1**  
**# pin A03: DMA1 Stream 6 Channel 3**  
**dma pin A02 0**  
**# pin A02: DMA1 Stream 1 Channel 3**  
**dma pin B05 0**  
**# pin B05: DMA1 Stream 5 Channel 5**  
**dma pin B07 0**  
**# pin B07: DMA1 Stream 3 Channel 2**  
**dma pin C09 0**  
**# pin C09: DMA2 Stream 7 Channel 7**  
**dma pin C08 0**  
**# pin C08: DMA2 Stream 2 Channel 0**  
**dma pin A09 0**  
**# pin A09: DMA2 Stream 6 Channel 0**  
**# 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 MOTOR\_STOP**  
**feature RX\_PARALLEL\_PWM**  
**feature RSSI\_ADC**

**feature LED\_STRIP**  
**feature OSD**  
**feature AIRMODE**  
**feature ANTI\_GRAVITY**  
**# serial**  
**serial 20 1 115200 57600 0 115200**  
**serial 0 0 115200 57600 0 115200**  
**serial 1 0 115200 57600 0 115200**  
**serial 2 0 115200 57600 0 115200**  
**serial 3 0 115200 57600 0 115200**  
**serial 4 0 115200 57600 0 115200**  
**serial 5 0 115200 57600 0 115200**  
**# mixer**  
**mixer HEX6X**  
**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  
# led  
led 0 8,8::CB:8  
led 1 9,8::CB:8  
led 2 10,8::CB:8  
led 3 11,8::CB:8  
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 0  
mode\_color 5 1 0  
mode\_color 5 2 0  
mode\_color 5 3 0  
mode\_color 5 4 0  
mode\_color 5 5 0  
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 0 900 900 0 0  
aux 1 0 0 900 900 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 0  
vtxtable channels 0  
vtxtable powerlevels 0  
vtxtable powervalues  
vtxtable powerlabels  
# 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 = 250  
set gyro\_lpf2\_type = PT1  
set gyro\_lpf2\_static\_hz = 500  
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 = 3  
set dyn\_notch\_q = 300  
set dyn\_notch\_min\_hz = 150  
set dyn\_notch\_max\_hz = 600  
set gyro\_lpf1\_dyn\_min\_hz = 250  
set gyro\_lpf1\_dyn\_max\_hz = 500  
set gyro\_lpf1\_dyn\_expo = 5  
set gyro\_filter\_debug\_axis = ROLL  
set acc\_hardware = AUTO  
set acc\_lpf\_hz = 10  
set acc\_trim\_pitch = 0  
set acc\_trim\_roll = 0  
set acc\_calibration = 158,-179,-30,1  
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 = AUTO  
set baro\_tab\_size = 21  
set baro\_noise\_lpf = 600  
set baro\_cf\_vel = 985  
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 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 = SBUS  
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\_rx\_snr = 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 = V202\_250K  
set rx\_spi\_bus = 0  
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\_disable\_gps = OFF  
set blackbox\_mode = NORMAL  
set min\_throttle = 1070  
set max\_throttle = 2000  
set min\_command = 1000  
set dshot\_idle\_value = 550  
set dshot\_burst = ON  
set dshot\_bidir = OFF  
set dshot\_bitbang = AUTO  
set dshot\_bitbang\_timer = AUTO  
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 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 = 430  
set vbat\_full\_cell\_voltage = 410  
set vbat\_min\_cell\_voltage = 330  
set vbat\_warning\_cell\_voltage = 350

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 = 170  
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 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 auto\_disarm\_delay = 5  
set gyro\_cal\_on\_first\_arm = OFF

set gps\_provider = NMEA  
set gps\_sbas\_mode = NONE  
set gps\_sbas\_integrity = OFF  
set gps\_auto\_config = ON  
set gps\_auto\_baud = OFF  
set gps\_ublox\_use\_galileo = OFF  
set gps\_ublox\_mode = AIRBORNE  
set gps\_set\_home\_point\_once = OFF  
set gps\_use\_3d\_speed = OFF  
set gps\_rescue\_angle = 32  
set gps\_rescue\_alt\_buffer = 15  
set gps\_rescue\_initial\_alt = 50  
set gps\_rescue\_descent\_dist = 200  
set gps\_rescue\_landing\_alt = 5  
set gps\_rescue\_landing\_dist = 10  
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 = 1100  
set gps\_rescue\_throttle\_max = 1600  
set gps\_rescue\_ascend\_rate = 500  
set gps\_rescue\_descend\_rate = 150  
set gps\_rescue\_throttle\_hover = 1280  
set gps\_rescue\_sanity\_checks = RESCUE\_SANITY\_ON  
set gps\_rescue\_min\_sats = 8  
set gps\_rescue\_min\_dth = 100  
set gps\_rescue\_allow\_arwing\_without\_fix = OFF  
set gps\_rescue\_alt\_mode = MAX\_ALT  
set gps\_rescue\_use\_mag = ON  
set deadband = 0  
set yaw\_deadband = 0  
set yaw\_control\_reversed = OFF  
set pid\_process\_denom = 1  
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 = 100  
set tlm\_inverted = OFF  
set tlm\_halfduplex = ON  
set frsky\_default\_lat = 0  
set frsky\_default\_long = 0  
set frsky\_gps\_format = 0

**set frsky\_unit = METRIC**  
**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 mavlink\_mah\_as\_heading\_divisor = 0**  
**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 ledstrip\_visual\_beeper = OFF**  
**set ledstrip\_visual\_beeper\_color = WHITE**  
**set ledstrip\_grb\_rgb = GRB**  
**set ledstrip\_profile = STATUS**  
**set ledstrip\_race\_color = ORANGE**  
**set ledstrip\_beacon\_color = WHITE**  
**set ledstrip\_beacon\_period\_ms = 500**  
**set ledstrip\_beacon\_percent = 50**  
**set ledstrip\_beacon\_armed\_only = OFF**  
**set ledstrip\_brightness = 100**  
**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\_ariming\_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\_warn\_rc\_smoothing = ON  
set osd\_warn\_fail\_safe = ON  
set osd\_warn\_launch\_control = ON  
set osd\_warn\_no\_gps\_rescue = ON  
set osd\_warn\_gps\_rescue\_disabled = ON  
set osd\_warn\_rssi = OFF  
set osd\_warn\_link\_quality = OFF  
set osd\_warn\_rssi\_dbm = OFF  
set osd\_warn\_over\_cap = OFF  
set osd\_rssi\_alarm = 20  
set osd\_link\_quality\_alarm = 80  
set osd\_rssi\_dbm\_alarm = -60  
set osd\_cap\_alarm = 2200  
set osd\_alt\_alarm = 100  
set osd\_distance\_alarm = 0  
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\_ah\_invert = OFF  
set osd\_logo\_on\_armed = OFF  
set osd\_logo\_on\_armed\_duration = 5  
set osd\_tim1 = 2560  
set osd\_tim2 = 2561  
set osd\_vbat\_pos = 2337  
set osd\_rssi\_pos = 234  
set osd\_link\_quality\_pos = 234  
set osd\_link\_tx\_power\_pos = 234  
set osd\_rssi\_dbm\_pos = 234  
set osd\_tim\_1\_pos = 234  
set osd\_tim\_2\_pos = 234  
set osd\_remaining\_time\_estimate\_pos = 234  
set osd\_flymode\_pos = 234  
set osd\_anti\_gravity\_pos = 234  
set osd\_g\_force\_pos = 234  
set osd\_throttle\_pos = 234  
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 = 2282

set osd\_mah\_drawn\_pos = 234  
set osd\_motor\_diag\_pos = 234  
set osd\_craft\_name\_pos = 234  
set osd\_display\_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 = 14665  
set osd\_avg\_cell\_voltage\_pos = 2401  
set osd\_pit\_ang\_pos = 234  
set osd\_rol\_ang\_pos = 234  
set osd\_battery\_usage\_pos = 234  
set osd\_disarmed\_pos = 234  
set osd\_nheading\_pos = 234  
set osd\_up\_down\_reference\_pos = 205  
set osd\_nvario\_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\_stat\_rtc\_date\_time = OFF  
set osd\_stat\_tim\_1 = OFF

set osd\_stat\_tim\_2 = ON  
set osd\_stat\_max\_spd = ON  
set osd\_stat\_max\_dist = OFF  
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 = OFF  
set osd\_stat\_bbox = ON  
set osd\_stat\_bb\_no = ON  
set osd\_stat\_max\_g\_force = OFF  
set osd\_stat\_max\_esc\_temp = OFF  
set osd\_stat\_max\_esc\_rpm = OFF  
set osd\_stat\_min\_link\_quality = OFF  
set osd\_stat\_flight\_dist = OFF  
set osd\_stat\_max\_fft = OFF  
set osd\_stat\_total\_flights = OFF  
set osd\_stat\_total\_time = OFF  
set osd\_stat\_total\_dist = OFF  
set osd\_stat\_min\_rssi\_dbm = OFF  
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 = AUTO  
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 system\_hse\_mhz = 8  
set task\_statistics = ON  
set debug\_mode = NONE  
set rate\_6pos\_switch = OFF  
set cpu\_overclock = OFF  
set pwr\_on\_arm\_grace = 5  
set enable\_stick\_arwing = OFF  
set vtx\_band = 0  
set vtx\_channel = 0  
set vtx\_power = 0  
set vtx\_low\_power\_disarm = OFF  
set vtx\_softserial\_alt = OFF  
set vtx\_freq = 0  
set vtx\_pit\_mode\_freq = 0



set gyro\_1\_spibus = 1  
set gyro\_1\_i2cBus = 0  
set gyro\_1\_i2c\_address = 0  
set gyro\_1\_sensor\_align = CW90  
set gyro\_1\_align\_roll = 0  
set gyro\_1\_align\_pitch = 0  
set gyro\_1\_align\_yaw = 900  
set gyro\_2\_bustype = SPI  
set gyro\_2\_spibus = 1  
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 = HYBRID  
set expresslrs\_model\_id = 255  
set scheduler\_relax\_rx = 25  
set scheduler\_relax\_osd = 25  
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 name = -  
set display\_name = -  
set position\_alt\_source = DEFAULT  
set position\_alt\_gps\_min\_sats = 10

```
set position_alt_baro_fallback_sats = 7
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 = 75
set dterm_lpf1_dyn_max_hz = 150
set dterm_lpf1_dyn_expo = 5
set dterm_lpf1_type = PT1
set dterm_lpf1_static_hz = 75
set dterm_lpf2_type = PT1
set dterm_lpf2_static_hz = 150
set dterm_notch_hz = 0
set dterm_notch_cutoff = 0
set vbat_sag_compensation = 0
set pid_at_min_throttle = ON
set anti_gravity_mode = SMOOTH
set anti_gravity_threshold = 250
set anti_gravity_gain = 3500
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 = 15
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 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 = 47**  
**set i\_pitch = 84**  
**set d\_pitch = 46**  
**set f\_pitch = 125**  
**set p\_roll = 45**  
**set i\_roll = 80**  
**set d\_roll = 40**  
**set f\_roll = 120**  
**set p\_yaw = 45**  
**set i\_yaw = 80**  
**set d\_yaw = 0**  
**set f\_yaw = 120**  
**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 = 30**  
**set d\_min\_pitch = 34**  
**set d\_min\_yaw = 0**  
**set d\_max\_gain = 37**  
**set d\_max\_advance = 20**  
**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 = 0**  
**set transient\_throttle\_limit = 0**  
**set feedforward\_transition = 0**  
**set feedforward\_averaging = OFF**  
**set feedforward\_smooth\_factor = 25**  
**set feedforward\_jitter\_factor = 7**  
**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 = 100
set simplified_i_gain = 100
set simplified_d_gain = 100
set simplified_pi_gain = 100
set simplified_dmax_gain = 100
set simplified_feedforward_gain = 100
set simplified_pitch_d_gain = 100
set simplified_pitch_pi_gain = 100
set simplified_dterm_filter = ON
set simplified_dterm_filter_multiplier = 100
rateprofile 0
# rateprofile 0
set rateprofile_name = -
set thr_mid = 50
set thr_expo = 0
set rates_type = ACTUAL
set quickrates_rc_expo = OFF
set roll_rc_rate = 7
set pitch_rc_rate = 7
set yaw_rc_rate = 7
set roll_expo = 0
set pitch_expo = 0
set yaw_expo = 0
set roll_srate = 67
set pitch_srate = 67
set yaw_srate = 67
set tpa_rate = 65
set tpa_breakpoint = 1350
set tpa_mode = D
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
#
```