

Gyro Accel Mag Baro GPS Serial

No dataflash chip found
Profile 1
Disconnect

2016-03-26 @ 21:23:20 - Unique device ID received - 0x670ff5751777167244953

Setup
Ports
Configuration
Failsafe
PID Tuning
Receiver
Modes
Adjustments
Servos
GPS
Motors
Race Transponder
LED Strip
Sensors
Tethered Logging
Blackbox

Configuration

Note: Not all combinations of features are valid. When the flight controller firmware detects invalid feature combinations conflicting features will be disabled.
Note: Configure serial ports **before** enabling the features that will use the ports.

Mixer
Quad X

ESC/Motor Features

☒ MOTOR_STOP

Don't spin the motors when armed

☐ ONESHOT125

ONESHOT ESC support

☒

Disarm motors regardless of throttle value (When arming via AUX channel)

5

Disarm motors after set delay(Seconds) (Requires MOTOR_STOP feature)

1150

Minimum Throttle

1500

Middle Throttle (RC inputs center value)

2000

Maximum Throttle

972

Minimum Command

Board and Sensor Alignment

0

Roll Degrees

GYRO Alignment

Default

Accelerometer Trim

0

Accelerometer Roll Trim

Save and Reboot

Port utilization: D: 1% U: 0% Packet error: 0 I2C error: 0 Cycle Time: 993

1.2.1

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Configuration

Board and Sensor Alignment

0

Roll Degrees

GYRO Alignment

Default

0

Pitch Degrees

ACCEL Alignment

Default

0

Yaw Degrees

MAG Alignment

Default

Receiver Mode

☒ RX_PPM

PPM RX input

☐ RX_SERIAL

Serial-based receiver (SPEKTRUM, SBUS, SUMD)

☐ RX_PARALLEL_PWM

PWM RX input (one wire per channel)

☐ RX_MSP

MSP RX input (control via MSP port)

Serial Receiver Provider

Note: Remember to configure a Serial Port (via Ports tab) and choose a Serial Receiver Provider when using RX_SERIAL feature.

SPEKTRUM1024
SPEKTRUM2048
SBUS
SUMD

Accelerometer Trim

0

Accelerometer Roll Trim

0

Accelerometer Pitch Trim

Battery Voltage

☒ VBAT

Battery voltage monitoring

3.3

Minimum Cell Voltage

4.3

Maximum Cell Voltage

3.5

Warning Cell Voltage

110

Voltage Scale

0.0

Battery Voltage

Current Sensor

☐ CURRENT_METER

Battery current monitoring

Save and Reboot

Port utilization: D: 1% U: 0% Packet error: 0 I2C error: 0 Cycle Time: 1001

1.2.1

CLEANFLIGHT
CONFIGURATOR 1.2.1

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Setup Ports **Configuration** Failsafe PID Tuning Receiver Modes Adjustments Servos GPS Motors Race Transponder LED Strip Sensors Tethered Logging Blackbox

XBUS_MODE_B_RJ01
IBUS

Offset in millivolt steps
0.00 Battery Current
Enable support for legacy Multiwii MSP current output

RSSI (Signal Strength)
RSSI_ADC Analog RSSI input

System configuration
Note: Changing this may require PID re-tuning.
2000 Flight Controller Loop Time
500 Cycles/Sec (Hz)

GPS
Note: Remember to configure a Serial Port (via Ports tab) when using GPS feature.
GPS for navigation and telemetry
NMEA Protocol
Auto-detect Ground Assistance Type
0 Magnetometer Declination [deg]

Other Features
INFLIGHT_ACC_CAL In-flight level calibration
SERVO_TILT Servo gimbal
SOFTSERIAL Enable CPU based serial ports
SONAR Sonar
TELEMETRY Telemetry output
3D 3D mode (for use with reversible ESCs)

Save and Reboot

Port utilization: D: 1% U: 0% Packet error: 0 I2C error: 0 Cycle Time: 991

DE 21:33 26.03.2016

CLEANFLIGHT
CONFIGURATOR 1.2.1

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Setup Ports **Configuration** Failsafe PID Tuning Receiver Modes Adjustments Servos GPS Motors Race Transponder LED Strip Sensors Tethered Logging Blackbox

NMEA Protocol
Auto-detect Ground Assistance Type
0 Magnetometer Declination [deg]

3D
1406 3D Deadband Low
1514 3D Deadband High
1460 3D Neutral
50 3D Deadband Throttle

Other Features
SONAR Sonar
TELEMETRY Telemetry output
3D 3D mode (for use with reversible ESCs)
LED_STRIP Multi-color RGB LED strip support
DISPLAY OLED Screen Display
BLACKBOX Blackbox flight data recorder
CHANNEL_FORWARDING Forward aux channels to servo outputs
TRANSPONDER Race Transponder

Save and Reboot

Port utilization: D: 1% U: 0% Packet error: 0 I2C error: 0 Cycle Time: 1003

DE 21:33 26.03.2016