resource MOTOR 1 C09 resource MOTOR 2 C08 resource MOTOR 3 C07 resource MOTOR 4 C06	<>	resource MOTOR 1 C07 resource MOTOR 2 C06 resource MOTOR 3 C09 resource MOTOR 4 C08
serial 4 2 115200 57600 0 115200	<>	serial 4 0 115200 57600 0 115200
aux 4 40 3 1600 2100 0 0	<>	aux 4 40 3 1700 2100 0 0
vtxtable bands 0 vtxtable channels 0 vtxtable powerlevels 0 vtxtable powervalues vtxtable powerlabels	<>	vtxtable bands 6 vtxtable channels 8 vtxtable band 1 BOSCAM_A A CUSTOM 5865 5845 5 » 825 5805 5785 5765 5745 5725 vtxtable band 2 BOSCAM_B B CUSTOM 5733 5752 5 » 771 5790 5809 5828 5847 5866 vtxtable band 3 BOSCAM_E E CUSTOM 5705 5685 5 » 665 5645 5885 5905 5925 5945 vtxtable band 4 FATSHARK F CUSTOM 5740 5760 5 » 780 5800 5820 5840 5860 5880 vtxtable band 5 RACEBAND R CUSTOM 5658 5695 5 » 732 5769 5806 5843 5880 5917 vtxtable band 6 BAND_D D CUSTOM 5362 5399 5 » 436 5473 5510 5547 5584 5621 vtxtable powerlevels 5 vtxtable powervalues 25 100 200 400 600 vtxtable powerlabels 25 100 200 400 600
set gyro_lpf1_static_hz = 300	<>	set gyro_lpf1_static_hz = 0
set gyro_lpf2_static_hz = 600	<>	set gyro_lpf2_static_hz = 500
set dyn_notch_count = 0 set dyn_notch_q = 500	<>	set dyn_notch_count = 1 set dyn_notch_q = 600
set gyro_lpf1_dyn_min_hz = 300 set gyro_lpf1_dyn_max_hz = 600	<>	set gyro_lpf1_dyn_min_hz = 250 set gyro_lpf1_dyn_max_hz = 500
set acc_calibration = -41,3,-36,1	<>	set acc_calibration = -61,0,-7,1
set min_check = 1150	<>	set min_check = 1050
set blackbox_sample_rate = 1/4	<>	set blackbox_sample_rate = 1/8
set motor_output_reordering = 2,3,0,1,4,5,6,7	<>	set motor_output_reordering = 0,1,2,3,4,5,6,7
set deadband = 20 set yaw_deadband = 15	<>	set deadband = 0 set yaw_deadband = 0
set simplified_gyro_filter_multiplier = 120	<>	set simplified_gyro_filter_multiplier = 100
set osd_vbat_pos = 2082	<>	set osd_vbat_pos = 2083
set osd_tim_2_pos = 2114	<>	set osd_tim_2_pos = 2115
set osd_vtx_channel_pos = 234	<>	set osd_vtx_channel_pos = 436
set osd_current_pos = 234	<>	set osd_current_pos = 259
profile 0	<>	profile 1
# profile 0	<>	# profile 1
set dterm_lpf1_dyn_min_hz = 67 set dterm_lpf1_dyn_max_hz = 135	<>	set dterm_lpf1_dyn_min_hz = 75 set dterm_lpf1_dyn_max_hz = 150
set dterm_lpf1_static_hz = 67	<>	set dterm_lpf1_static_hz = 75
set dterm_lpf2_static_hz = 135	<>	set dterm_lpf2_static_hz = 150
set p_pitch = 50	<>	set p_pitch = 58

set i_pitch = 99 set d_pitch = 50 set f_pitch = 101 set p_roll = 48 set i_roll = 95 set d_roll = 44 set f_roll = 97 set p_yaw = 48 set i_yaw = 95		set i_pitch = 105 set d_pitch = 46 set f_pitch = 125 set p_roll = 56 set i_roll = 100 set d_roll = 40 set f_roll = 120 set p_yaw = 56 set i_yaw = 100
set f_yaw = 97 set angle_level_strength = 50	<>	set f_yaw = 120 set angle_level_strength = 80
set d_min_roll = 37 set d_min_pitch = 42	<>	set d_min_roll = 39 set d_min_pitch = 44
set thrust_linear = 0	<>	set thrust_linear = 20
set feedforward_jitter_factor = 7	<>	set feedforward_jitter_factor = 12
set simplified_master_multiplier = 90 set simplified_i_gain = 110 set simplified_d_gain = 140 set simplified_pi_gain = 120 set simplified_dmax_gain = 50 set simplified_feedforward_gain = 90	<>	set simplified_master_multiplier = 100 set simplified_i_gain = 100 set simplified_d_gain = 130 set simplified_pi_gain = 125 set simplified_dmax_gain = 15 set simplified_feedforward_gain = 100
set simplified_dterm_filter_multiplier = 90	<>	set simplified_dterm_filter_multiplier = 100