# dump

# version
# Betaflight / STM32F405 (S405) 4.2.4 Oct 20 2020 / 08:18:45 (fbcaf8c50) MSP API: 1.43
# config: manufacturer\_id: AIKO, board\_name: AIKONF4, version: 3a35e73b, date: 2019-09-30T05:46:12Z

# start the command batch
batch start

board\_name AIKONF4
manufacturer\_id AIKO

# name: Tigers.i

# resources
resource BEEPER 1 B05
resource MOTOR 1 C09
resource MOTOR 2 C08
resource MOTOR 3 C07
resource MOTOR 4 C06
resource MOTOR 5 B00
resource MOTOR 6 B01
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 B06
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 B06
resource SERIAL\_TX 1 NONE
resource SERIAL\_TX 2 A02
resource SERIAL\_TX 3 B10
resource SERIAL\_TX 4 A00
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 A09
resource SERIAL\_TX 12 NONE
resource SERIAL\_RX 1 A10
resource SERIAL\_RX 2 A03
resource SERIAL\_RX 3 B11
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 NONE
resource SERIAL\_RX 12 A01
resource INVERTER 1 C00
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 B04
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 B13
resource SPI\_SCK 3 C10
resource SPI\_MISO 1 A06
resource SPI\_MISO 2 B14
resource SPI\_MISO 3 C11
resource SPI\_MOSI 1 A07
resource SPI\_MOSI 2 B15
resource SPI\_MOSI 3 C12
resource ESCSERIAL 1 B06
resource CAMERA\_CONTROL 1 B03
resource ADC\_BATT 1 C02
resource ADC\_RSSI 1 C03
resource ADC\_CURR 1 C01
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 B12
resource OSD\_CS 1 A15
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 GYRO\_EXTI 1 C04
resource GYRO\_EXTI 2 NONE
resource GYRO\_CS 1 A04
resource GYRO\_CS 2 NONE
resource USB\_DETECT 1 D02
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 B03 AF1
# pin B03: TIM2 CH2 (AF1)
timer C06 AF3
# pin C06: TIM8 CH1 (AF3)
timer C07 AF3
# pin C07: TIM8 CH2 (AF3)
timer C08 AF3
# pin C08: TIM8 CH3 (AF3)
timer C09 AF3
# pin C09: TIM8 CH4 (AF3)
timer B00 AF2
# pin B00: TIM3 CH3 (AF2)
timer B01 AF2
# pin B01: TIM3 CH4 (AF2)
timer A09 AF1
# pin A09: TIM1 CH2 (AF1)
timer A02 AF3
# pin A02: TIM9 CH1 (AF3)
timer A03 AF3
# pin A03: TIM9 CH2 (AF3)
timer A00 AF2
# pin A00: TIM5 CH1 (AF2)
timer A01 AF2
# pin A01: TIM5 CH2 (AF2)
timer B06 AF2
# pin B06: TIM4 CH1 (AF2)

# dma
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 1
# ADC 1: DMA2 Stream 4 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 B03 0
# pin B03: DMA1 Stream 6 Channel 3
dma pin C06 0
# pin C06: DMA2 Stream 2 Channel 0
dma pin C07 0
# pin C07: DMA2 Stream 2 Channel 0
dma pin C08 0
# pin C08: DMA2 Stream 2 Channel 0
dma pin C09 0
# pin C09: DMA2 Stream 7 Channel 7
dma pin B00 0
# pin B00: DMA1 Stream 7 Channel 5
dma pin B01 0
# pin B01: DMA1 Stream 2 Channel 5
dma pin A09 0
# pin A09: DMA2 Stream 6 Channel 0
dma pin A02 NONE
dma pin A03 NONE
dma pin A00 0
# pin A00: DMA1 Stream 2 Channel 6
dma pin A01 0
# pin A01: DMA1 Stream 4 Channel 6
dma pin B06 0
# pin B06: DMA1 Stream 0 Channel 2

# 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

# 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 -DYNAMIC\_FILTER
feature RX\_SERIAL
feature TELEMETRY
feature OSD
feature AIRMODE
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 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 TAER1234

# serial
serial 20 1 115200 57600 0 115200
serial 0 0 115200 57600 0 115200
serial 1 64 115200 57600 0 115200
serial 2 0 115200 57600 0 115200
serial 3 1 115200 57600 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 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 1700 2100 0 0
aux 1 13 2 1700 2100 0 0
aux 2 35 1 1700 2100 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\_lowpass\_type = PT1
set gyro\_lowpass\_hz = 200
set gyro\_lowpass2\_type = PT1
set gyro\_lowpass2\_hz = 325
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\_width\_percent = 8
set dyn\_notch\_q = 120
set dyn\_notch\_min\_hz = 150
set dyn\_notch\_max\_hz = 600
set dyn\_lpf\_gyro\_min\_hz = 260
set dyn\_lpf\_gyro\_max\_hz = 650
set gyro\_filter\_debug\_axis = ROLL
set acc\_hardware = NONE
set acc\_lpf\_hz = 10
set acc\_trim\_pitch = 0
set acc\_trim\_roll = 0
set acc\_calibration = 0,0,0,0
set align\_mag = DEFAULT
set mag\_align\_roll = 0
set mag\_align\_pitch = 0
set mag\_align\_yaw = 0
set mag\_bustype = SPI
set mag\_i2c\_device = 0
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 = NONE
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 = 12
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\_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 = AUTO
set rc\_smoothing\_auto\_smoothness = 10
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\_rx\_snr = OFF
set airmode\_start\_throttle\_percent = 25
set rx\_min\_usec = 885
set rx\_max\_usec = 2115
set serialrx\_halfduplex = OFF
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\_p\_ratio = 32
set blackbox\_device = SPIFLASH
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 = 550
set dshot\_burst = ON
set dshot\_bidir = ON
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 = 14
set thr\_corr\_value = 0
set thr\_corr\_angle = 800
set failsafe\_delay = 4
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 = 20
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 = 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 = ON
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\_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\_arming\_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 = 2
set runaway\_takeoff\_prevention = ON
set runaway\_takeoff\_deactivate\_delay = 500
set runaway\_takeoff\_deactivate\_throttle\_percent = 20
set thrust\_linear = 0
set transient\_throttle\_limit = 0
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 = 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 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 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 sdcard\_detect\_inverted = OFF
set sdcard\_mode = OFF
set sdcard\_dma = 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 = IMPERIAL
set osd\_warn\_arming\_disable = ON
set osd\_warn\_batt\_not\_full = OFF
set osd\_warn\_batt\_warning = OFF
set osd\_warn\_batt\_critical = ON
set osd\_warn\_visual\_beeper = ON
set osd\_warn\_crash\_flip = ON
set osd\_warn\_esc\_fail = OFF
set osd\_warn\_core\_temp = ON
set osd\_warn\_rc\_smoothing = OFF
set osd\_warn\_fail\_safe = ON
set osd\_warn\_launch\_control = ON
set osd\_warn\_no\_gps\_rescue = OFF
set osd\_warn\_gps\_rescue\_disabled = OFF
set osd\_warn\_rssi = OFF
set osd\_warn\_link\_quality = 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\_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 = 2400
set osd\_rssi\_pos = 2490
set osd\_link\_quality\_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 = 234
set osd\_mah\_drawn\_pos = 2432
set osd\_motor\_diag\_pos = 234
set osd\_craft\_name\_pos = 2070
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 = 2464
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\_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\_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 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 scheduler\_optimize\_rate = AUTO
set enable\_stick\_arming = OFF
set vtx\_band = 0
set vtx\_channel = 0
set vtx\_power = 0
set vtx\_low\_power\_disarm = OFF
set vtx\_freq = 0
set vtx\_pit\_mode\_freq = 0
set vtx\_halfduplex = ON
set vtx\_spi\_bus = 0
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 max7456\_preinit\_opu = OFF
set displayport\_msp\_col\_adjust = 0
set displayport\_msp\_row\_adjust = 0
set displayport\_msp\_serial = 0
set displayport\_msp\_attrs = 0,0,0,0
set displayport\_msp\_use\_device\_blink = OFF
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 frsky\_spi\_autobind = OFF
set frsky\_spi\_tx\_id = 0,0
set frsky\_spi\_offset = 0
set frsky\_spi\_bind\_hop\_data = 0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0
set frsky\_x\_rx\_num = 0
set frsky\_spi\_a1\_source = VBAT
set cc2500\_spi\_chip\_detect = ON
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\_button\_resistance = 450,270,150,68,0
set camera\_control\_inverted = OFF
set rangefinder\_hardware = NONE
set pinio\_config = 1,1,1,1
set pinio\_box = 255,255,255,255
set usb\_hid\_cdc = OFF
set usb\_msc\_pin\_pullup = ON
set flash\_spi\_bus = 2
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 = CW0
set gyro\_1\_align\_roll = 0
set gyro\_1\_align\_pitch = 0
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\_overclock = ON
set i2c2\_pullup = OFF
set i2c2\_overclock = ON
set i2c3\_pullup = OFF
set i2c3\_overclock = ON
set mco2\_on\_pc9 = OFF
set timezone\_offset\_minutes = 0
set gyro\_rpm\_notch\_harmonics = 3
set gyro\_rpm\_notch\_q = 500
set gyro\_rpm\_notch\_min = 100
set dterm\_rpm\_notch\_harmonics = 0
set dterm\_rpm\_notch\_q = 500
set dterm\_rpm\_notch\_min = 100
set rpm\_notch\_lpf = 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 = OFF
set stats\_total\_flights = 0
set stats\_total\_time\_s = 0
set stats\_total\_dist\_m = 0
set name = Tigers.i
set display\_name = -
set position\_alt\_source = DEFAULT
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 dyn\_lpf\_dterm\_min\_hz = 91
set dyn\_lpf\_dterm\_max\_hz = 221
set dyn\_lpf\_dterm\_curve\_expo = 5
set dterm\_lowpass\_type = PT1
set dterm\_lowpass\_hz = 150
set dterm\_lowpass2\_type = PT1
set dterm\_lowpass2\_hz = 195
set dterm\_notch\_hz = 0
set dterm\_notch\_cutoff = 0
set vbat\_pid\_gain = OFF
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 feedforward\_transition = 0
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 = 100
set iterm\_limit = 400
set pidsum\_limit = 500
set pidsum\_limit\_yaw = 400
set yaw\_lowpass\_hz = 0
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 = 46
set i\_pitch = 90
set d\_pitch = 38
set f\_pitch = 95
set p\_roll = 42
set i\_roll = 85
set d\_roll = 35
set f\_roll = 90
set p\_yaw = 45
set i\_yaw = 90
set d\_yaw = 0
set f\_yaw = 90
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 = 23
set d\_min\_pitch = 25
set d\_min\_yaw = 0
set d\_min\_boost\_gain = 37
set d\_min\_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 ff\_interpolate\_sp = AVERAGED\_2
set ff\_spike\_limit = 60
set ff\_max\_rate\_limit = 100
set ff\_smooth\_factor = 37
set ff\_boost = 15
set idle\_min\_rpm = 0
set idle\_adjustment\_speed = 50
set idle\_p = 50
set idle\_pid\_limit = 200
set idle\_max\_increase = 150
set level\_race\_mode = OFF

rateprofile 0

# rateprofile 0
set rateprofile\_name = -
set thr\_mid = 50
set thr\_expo = 0
set rates\_type = BETAFLIGHT
set roll\_rc\_rate = 125
set pitch\_rc\_rate = 125
set yaw\_rc\_rate = 160
set roll\_expo = 10
set pitch\_expo = 10
set yaw\_expo = 15
set roll\_srate = 72
set pitch\_srate = 72
set yaw\_srate = 30
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

# end the command batch
batch end