**AQ32 4s (Y6 FPV / meiner):**

#define BATT\_ANALOG\_INPUT Port2Pin('C', 2)

#define BATT\_R\_HIGH 9.88

#define BATT\_R\_LOW 1.48

#define BATT\_DIODE\_LOSS 0.8

static byte receiverPinPPM = Port2Pin('D', 15); //Standard

**AQ32 v2 3S (mein Mini):**

hottv4Init(&Serial2);

#define BATT\_ANALOG\_INPUT Port2Pin('C', 0) //Standard

#define BATT\_R\_HIGH 10.0 // Standard

#define BATT\_R\_LOW 1.5

#define BATT\_DIODE\_LOSS 0.0

static byte receiverPinPPM = Port2Pin('D', 15); //Standard

**AQ32 3s (Quad X, Papa):**

#define BATT\_ANALOG\_INPUT Port2Pin('C', 0) //Standard

#define BATT\_R\_HIGH 10.0 // Standard

#define BATT\_R\_LOW 1.5

#define BATT\_DIODE\_LOSS 0.0

static byte receiverPinPPM = Port2Pin('D', 15); //Standard

Failsafe Throttle: 1300

**AQ32 FPV 3s (Quad X, Papa):**

#define BATT\_ANALOG\_INPUT Port2Pin('C',2)

#define BATT\_R\_HIGH 10.04 //5.6 onboard Widerstand

#define BATT\_R\_LOW 1.48 //1.5 onboard Widerstand

#define BATT\_DIODE\_LOSS 0.8

static byte receiverPinPPM = Port2Pin('D', 15); //Standard

Failsafe Throttle: 1520

**AQ Mini Shield 4s (Mini Quad, Papa):**

Attitude PIDs: P 40, I 0, D -200

**Brushless Gimbal (Meins, MK):**

* Reverse Z-Axis + Swap X/Y-Axis aktivieren
* Hard-coded sensor orientation:

sensorDef.Acc[PITCH].dir = 1;

sensorDef.Gyro[PITCH].dir = -1;

sensorDef.Gyro[ROLL].dir = -1;

**AQ32 Problemboard:**

#define BATT\_ANALOG\_INPUT Port2Pin('C', 0) //Standard

#define BattCustomConfig DEFINE\_BATTERY(0, BATT\_ANALOG\_INPUT, 15.8, 0, BM\_NOPIN, 0, 0)

static byte receiverPinPPM = Port2Pin('D', 13);