

Parameter	Range	Values	Type	Default	Description	Constraints/notes			
COM_CPU_MAX	-1 > 100 (1)								
IMU_GYRO_RATEMAX	100 > 2000	100, 250, 400, 800,1000, 2000	INT32	400	Gyro control data maximum publication rate (inner loop rate) in HZ				
EKF2_MAG_DECL			FLOAT	0	Magnetic declination				
RTL_RETURN_ALT	0 > 150 (0.5)		FLOAT	60	Return mode return altitude. Default minimum altitude above destination (e.g. home, safe point, landing pattern) for return flight.	This is affected by RTL_MIN_DIST and RTL_CONE_ANG.			
RTL_DESCEND_ALT	2 > 100 (0.5)		FLOAT	30	Return mode loiter altitude in M. Descend to this altitude (above destination position) after return, and wait for time defined in RTL_LAND_DELAY. Land (i.e. slowly descend) from this altitude if autolanding allowed.				
MPC_XY_VEL_D_ACC	0.1 > 2.0		FLOAT	0.2	Differential gain for horizontal velocity error. Small values help reduce fast oscillations. If value is too big oscillations will appear again				
MPC_XY_VEL_P_ACC	1.2 > 5.0		FLOAT	1.8	Proportional gain for horizontal velocity error				