Common Params

To Mirror Inav (Thr=1 Servo1=3 Servo2=4)

SERVO1_FUNCTION = 70 (throttle)
SERVO2_FUNCTION = 0 (disabled)
SERVO3_FUNCTION = 77 (AIL)
SERVO4_FUNCTION = 78 (ELE)
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param set RCMAP_PITCH = 3
param set RCMAP_ROLL = 2
param set RCMAP_THROTTLE = 1
param set RCMAP_YAW = 4

(Make sure RC Calibration sets a deadzone > 0). Default should be at least 30.

param set COMPASS_USE 0

Tuning to not fly bad
param set ACRO_PITCH_RATE 220 (deg/s)
param set ACRO_ROLL_RATE 280 (deg/s)

After running autotune, you need to SET RLL2SRV_RMAX and PTCH2SRV_RMAX_* to 0 as they override ACRO_PITCH_RATE and ACRO_ROLL_RATE

param set AUTOTUNE_LEVEL 7 (More aggressive than the default of 6, makes tune better)
param set LIM_ROLL_CD 4500 (centidegrees -- max roll angle in assisted modes)
param set LIM_PITCH_MAX 3000 (centidegrees - max pitch angle when ascending at max throttle)
param set LIM_PITCH_MIN 2000 (centidegrees - max pitch angle when descending at min throttle)
param set THR_MAX 80 (80% of max pwm)
param set SERVO_AUTO_TRIM 1

Optional
param set ALT_HOLD_RTL -1 (fly back at whatever the engaged alt is)
param set ARMING_CHECK 12314 (baro ahrs gps)
param set ARMING_RUDDER 2 (disarm and arm on elevon planes)

BATT_MONITOR 4 (Enable vbat / current sensing)
param set OSD_TYPE 1 (MAX7456)
param set osd_font 1 (clarity)
param set RSSI_TYPE 2 (RC Chan PWM)
param set RSSI_CHANNEL 8 (or whatever)

Speedybee APM Notes

param set AHRS_ORIENTATION 2 (yaw90) usb towards nose of craft
param set SERIAL4_BAUD 19 (bluetooth support)
param set SERIAL4_PROTOCOL 1 (mavlink 1.0)
param set SERIAL3_BAUD 38 (GPS) (wired to uart3)
param SERIAL3_PROTOCOL 5 (GPS)

DYSF4PRO APM Notes

- I2C baro goes on uart3 (not the serial port)
- Sbus RX goes to PPM pin

param set SERIAL3_BAUD 38 (GPS)
param set SERIAL3_PROTOCOL 5 (GPS wired to uart6)

MISC

UART MAP:

1 USB
2 GPS1
3 telem1
4 telem2
5 GPS 2
6 AUX