Load Motor Layout

QuadroCopter x mode (seçiniz)

Receiver Test

Ekrandaki eksenleri kumandanız yardımı ile hepsini 0 şeklinde ayarlayınız.

Mode Settings

Self-Level = Stick

Link Roll Pitch: YES

Auto Disarm= YES

Sat or CPPM :NO

Stick Scaling

Roll (Ail) = 10

Pitch (Ele)=10

Yaw(Rud)=10

Throttle=100

Misc. Settings

Minimum throttle=10

Height Dampening=0

Height D. Limit=30

Servo Filter=50

Pi Editor

Axis:Roll (Aileron)

P Gain = 150

P Limit= 100

I Gain = 50

I Limit=20

Axis:Roll (Elevator)

P Gain = 150

P Limit= 100

I Gain = 50

I Limit=20

Axis:Roll (Rudder)

P Gain = 150

P Limit= 20

I Gain = 20

I Limit=10

Self-Level Settings

P Gain = 100

P Limit =20

ACC Trim Roll =0

ACC Trim Pitch =0