My Quad yaws and or banks near full throttle! Is that normal? What to do against that?

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At full throttle (more than 85%), my quad turn on yaw axis alone.

First of all, lets explain why Silverware often has problems near full throttle. Silverware uses all power available from the motors on full throttle (with stock settings), there is no space for corrections with stock settings - but if all your motors and props are perfect, you are able to control the quad and have no issues.

But if not, you get the mentioned problems.

How to solve that? The hovercrest with many different motors made by different companies, and sometimes, the ccw and cw motors are a bit different, and can cause this.

In config.h there is the option #define MIX_LOWER_THROTTLE, which will lower throttle. You can add these defines in config.h around line 141:

```
#define MIX_LOWER_THROTTLE
#define MIX_THROTTLE_REDUCTION_PERCENT 30
```

Another way would be to change the pid limits to make yaw have higher priority. In pid.c (for troubleshooting) and that there is no dust/dirt/hair around the motor shaft!

Quote:

How to solve that? Here is a text, freely copied from a RCGroups Post by Silverxxx

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