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

t Emmbe caused by off center CG, or unmatched motors, or quad not straight. All motors of the party of the pa

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That be remanded in the table of table of

FWst of 915, ares a bit different since ware of the his "problems" near full throttle. Silverware all power available from the motors on full throttle (wirh stock settings), there is no spare throttle left for confections with stock settings), there is no spare throttle left for confections with stock settings, there is no spare throttle left for confections with stock settings and throttle.

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Hefine MIX_LOWER_THROTTLE

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Another way would be to change the pid limits to make yaw have higher priority. In file pid.c: How to solve that? Here is a text, freely copied from a RCGroups Post by Silverxxx output limit

const float outlimit[PIDNUMBER] = { 0.8 , 0.8 , 0.4 };

limit of integral term (abs)
const float integrallimit[PIDNUMBER] = { 0.8 , 0.8 , 0.4 };

The limit for roll and pitch is 0.8, and for yaw 0.4 in this case (defaults)

You could increase 0.4 in both places or reduce the other 2 axes limit, for example. sadly, this won't fix the unbalance, it will just transfer it to another axis, or make it less noticeable.

Just play with these values a bit and see what happens. Sometimes even reducing yaw limit (or one of the others) can help - a quad's behavior is not always logical...