

## My quad yaws unexpected at full throttle

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

It can be caused by off center CG, or unmatched motors, or quad not straight. All motors have to be absolutely vertical and parallel to each other!

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Permanent link:

The h8 comes with many different motors made by different companies, and sometime

<http://sirdomsen.diskstation.me/dokuwiki/doku.php?id=yawing&rev=1480239087>

FW motors are a bit different, and can cause this. Silverware often has "problems" near full throttle. Silverware

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First of all, lets explain why Silverware often has "problems" near full throttle. Silverware

all power available from the motors on full throttle (with stock settings), there is no spare throttle left

for corrections with stock settings - but if all your motors and props are perfect, you are still able to

control the quad and have no issues.

You can add these defines in config.h around line 141:

But if not, you get the mentioned problems!

```
#define MIX_LOWER_THROTTLE
```

Before doing the following steps, please make sure your props look good (replace if possible for

another way would be to change the pid limits to make yaw have higher priority. In file pid.c:

output limit that? Here is a text, freely copied from a [RCGroups Post by Silverxxx](#)

```
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...