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 quad not straight. All motors of the parts of

ermanent link:

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FW motors are a bit different jand care of ten has "problems" near full throttle. Silverwar 1 ast update: 2016/11/27 10:34 all power available from the motors on full throttle (with stock settings), there is no spare throttle EBATEOL THE GROW AND HOVE LOSS MAX throttle.

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#ENGINE THE POTTOWED BETTER DESCRIPTION OF SOME OF THE POSSIBLE FOR SOME OF THE POSSIBLE FOR THE POSSIBLE FO Anothes wax i would be to change the gigstion its its imake you wheave highes priority. In file pid.c:

Ploto 45 1500 He 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...