



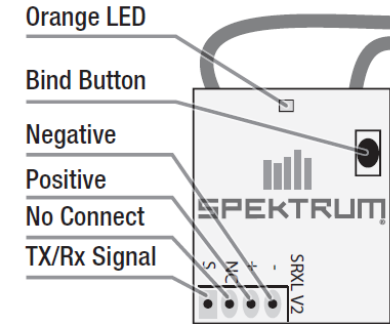
BETIAN GPS
BN-220, BN280



PIN	PIN Name	I/O	Description
1	1PPS	O	1 Pulse Per Second when 3D fixed
2	GND	G	Ground
3	TX	O	TTL Serial Data Output.
4	RX	I	TTL Serial Data Input.
5	VCC	I	DC 3.6V - 5.5V supply input, Typical: 5.0V
6	BOOT	I	N.C.

LTM MODUL LoRa (9600 bps)

LORA 433 MHz
E32-TTL-100



RECEIVER SERIAL SRXL2

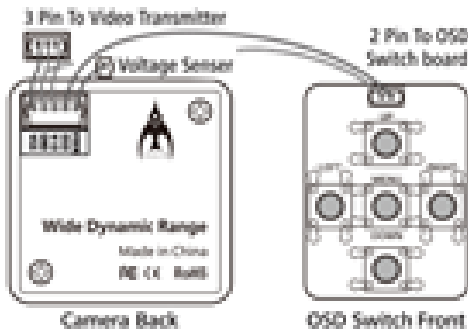
SPEKTRUM 4650

Binding

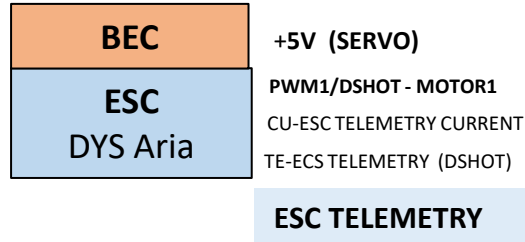
The SPM4650 requires a 3.3V – 8.4V volt

Tramp HV VTx

**VIDEO TRANSMITTER
TRAMP**



CAM OSD



5 Pin Harness
VCC DC 3-40V in (Red)
GND Ground Wire(Black)
VID Video-out(Yellow)
OSD OSD (White)
VSEN Voltage-Sensor(Blue)

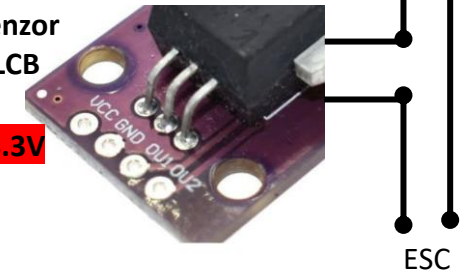
Connect the VSEN cable whenever you want to detect the voltage

AUX:

CH5 (C) – NO / ARM / ARM
CH6 (D) – MANUAL / RATE / HORIZON
CH7 (F) – NO / NAV CRUISE / NAV RTH
CH8 (B) – NO / ALTHOLD / NAV LOITER

**Current sensor
ACS758LCB**

VCC 3.3V



**IRC OSD
VIDEO IN (VTX)**



**CAMERA FOXEER
Arrow Mini Pro
(5-40V)**

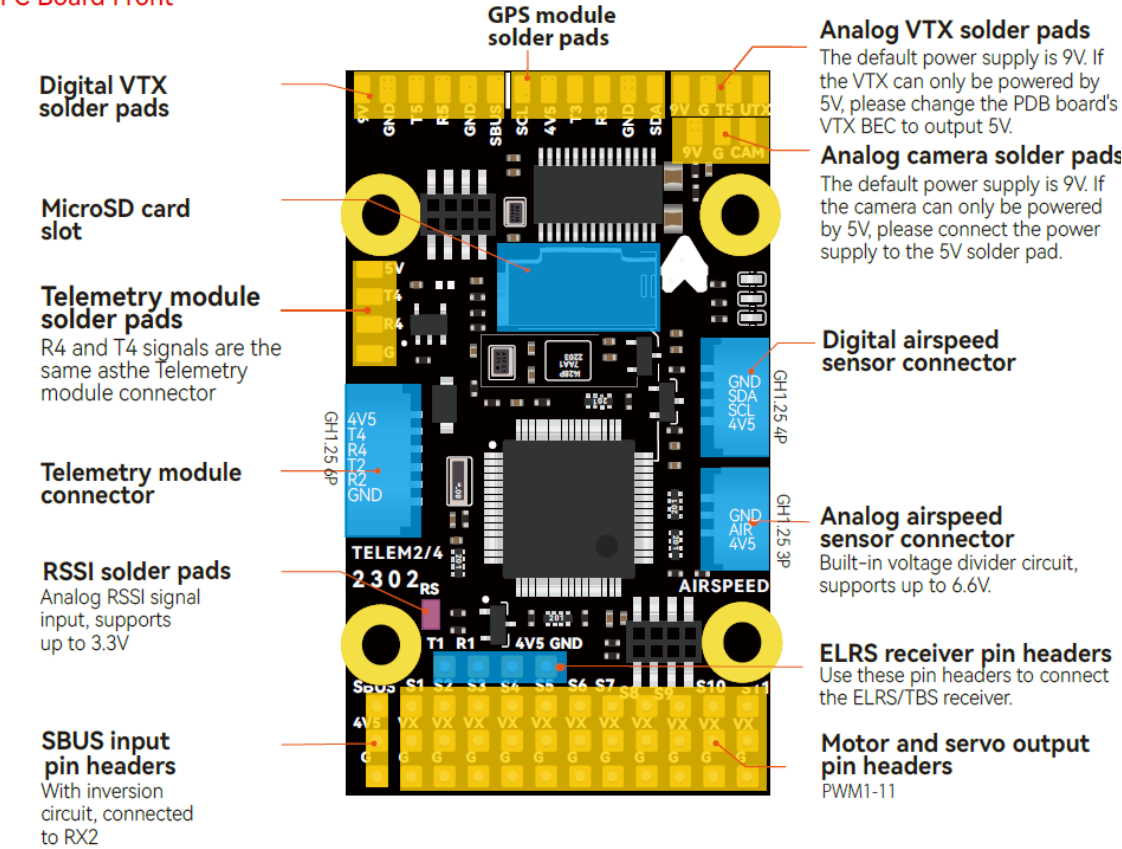
VIDEO OUT (CAM)

MCU: STM32F405,168MHz,1MB Flash
IMU: ICM-42688-P Baro: SPL006-001
Blackbox: SD Karta
Počet UARTů: 6 Počet I2C: 1
ADC: 4x (VBAT, Current, RSSI, Analog Airspeed)
PWM výstupy: 11 (+1 LED pad)
FC FW: iNAV/Ardupilot (SpeedyBeeF405WING)
Vstupní napětí: 7-36V (2-6S)
Senzor napětí: 1K:10K (Scale 1100 iNav, 11.0 Ardupilot)
Senzor proudu: 90A trval, 215 krátkodobě (Scale 195 iNav, 50 A/V Ardupilot)
FC BEC: 5.2V - 2.4A (3A krátkodobě) - Přijímač, GPS, Aispeed, Telemetrický modul, LED pásek
VTX BEC: 9(default)/12/5V - 1.8A (2.3A krátkodobě)
Servo BEC: 4.9(default)/6V/7.2V - 4.5A (5.5A krátkodobě)
Bezdrátový přenos: BLE mode (Speedybee App), Wi-Fi Mode, Bluetooth SPP mode (QGroundControl/MissionPlanner)
Integrovaný kontrolér pro LED
Velikost: 52x32x19mm

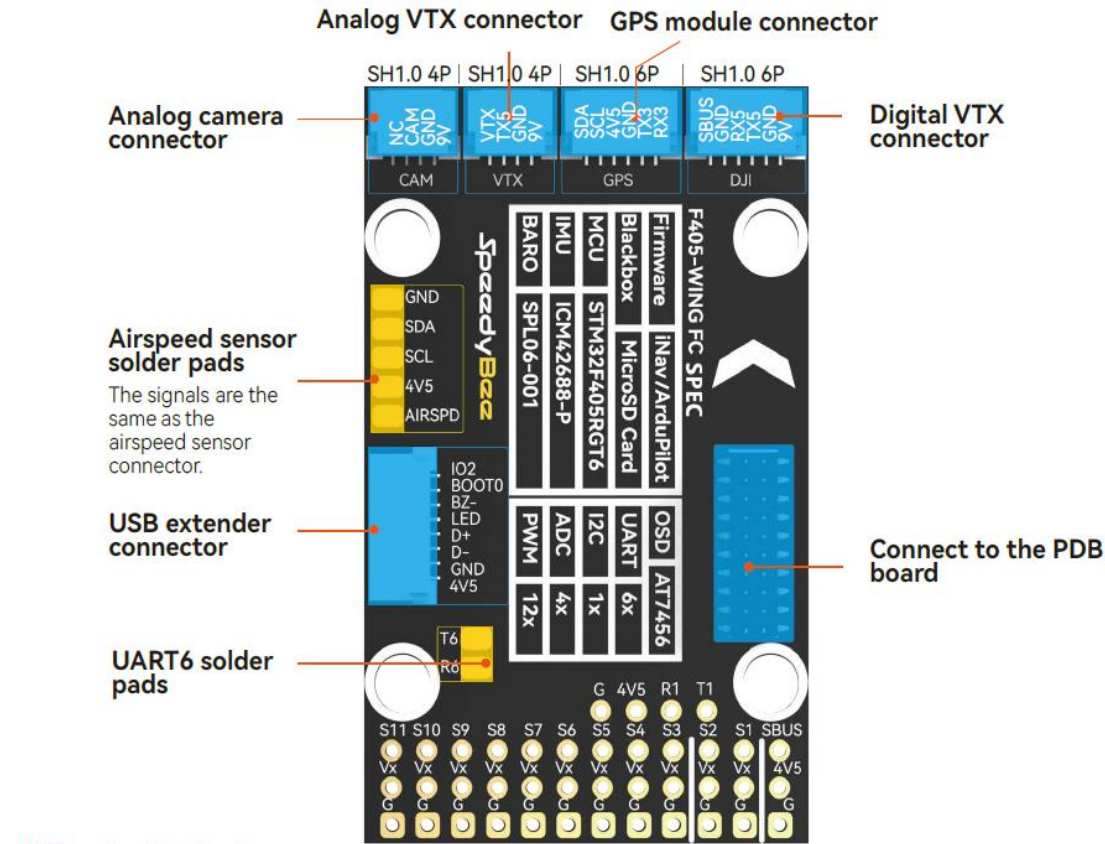
UART1	SRXL2 REC (TX1) SPEKTRUM 4650
UART2	ESC TELEMETRY (RX2)
UART3	GPS MODUL
UART4	LTM 9600 - TELEMETRY LORA
UART5	TRAMP MENU (TX5)
UART6	

Speedybee 1
F405 WING APP
iNAV:SpeedyBeeF405WING

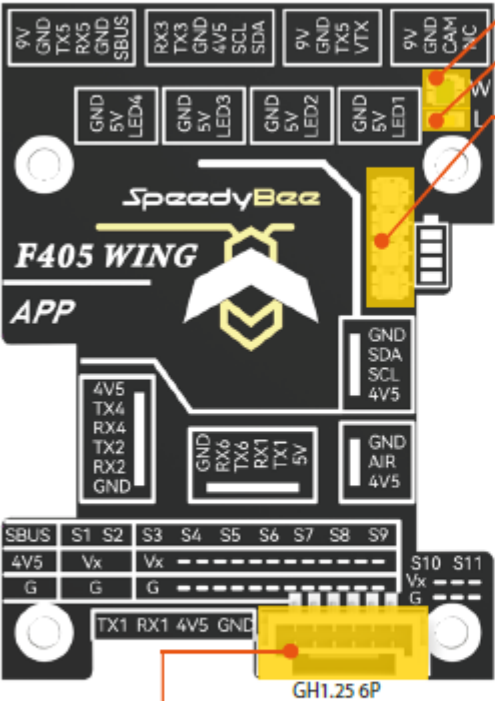
FC Board Front



FC Board Back



Wireless board Front

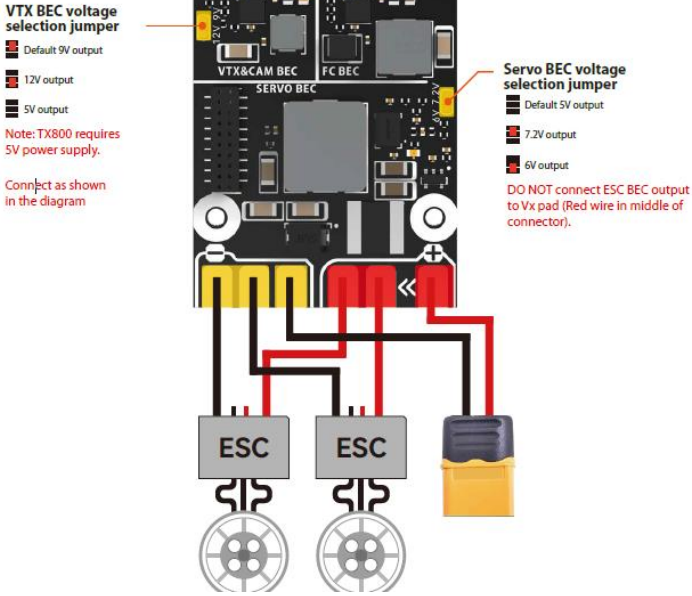


Reserved connector
Note: disconnect the UART6 jumper on the back of the wireless board to use TX6 RX6. TX1 RX1 shares the same signal as the ELRS/TBS receiver pin header.

- Wireless status indicator (RGB LED)
- LED mode indicator(orange LED)
- Battery LED: 4-level battery level indicator.
- Wireless status indicator (RGB LED)
The wireless board has built-in telemetry function , which includes 4 RF modes: Bluetooth BLE, Wi-Fi, classic Bluetooth SPP, and wireless off mode.
Green slow flashing :BLE not connected
Green solid:BLE connected successfully
White slow flashing :Wi-Fi not connected
White Solid:Wi-Fi connected successfully
Blue slow flashing:Classic Bluetooth SPP not connected
Blue Solid:Classic Bluetooth SPP not connected
RGB LED off: Wireless module turned off
Pressing the BOOT button for 6 seconds can switch between the 4 wireless modes. When the yellow LED flashes rapidly and the board automatically restarts, the switch is successful.
- LED mode indicator(orange LED):
Orange light always on:Solid orange LED means the 4 sets of LED strips are in SB_LED mode, controlled by the wireless chip.
A short press of the BOOT button cycles through different display effects when the FC is operating normally.
Orange light is off - Off orange LED indicates FC_LED mode, where the FC controls the 4 sets of LED strips directly.
Press and hold the BOOT button for 3 seconds to switch between FC_LED mode and SB_LED mode.

ADC			
VBAT	1K:10K divider builtin 0~30V	VBAT ADC ADC_CHANNEL_1	voltage scale 1100
CURR	0~3.3V	CURRENT_METER ADC ADC_CHANNEL_2	Current scale 195
AIRSPD	10K:10K divider builtin 0~6.6V	AIRSPEED ADC ADC_CHANNEL_3	Analog Airspeed
RSSI	0~3.3V	RSSI ADC ADC_CHANNEL_4	Analog RSSI
I2C			
I2C1	5V tolerant I/O	onboard Barometer	SPL06-001
		Compass	QMC5883 / HMC5883 / MAG3110 / LIS3MDL
		Digital Airspeed sensor	MS4525
		OLED	0.96"

PLUS board Front



● INAV mapping

UART			
USB		USB	
TX1 RX1	5V tolerant I/O	UART1	ELRS/TBS receiver
TX2 RX2 SBUS	5V tolerant I/O	SBUS pad	SBUS receiver, SBUS pad = RX2 with inverter
		TX2	SmartPort Telemetry,enable Softserial_Tx2
TX3 RX3	5V tolerant I/O	UART3	GPS
TX4 RX4	5V tolerant I/O	UART4	USER
TX5 RX5	5V tolerant I/O	UART5	DJI OSD/VTX
TX6 RX6	5V tolerant I/O	UART6	Onboard wireless controller

Speedybee 2
F405 WING APP
INAV:SpeedyBeeF405WING

+ & - : LiPO & ESC power pads, 9~30V DC.
S1/S2: ESC signal for motor 1 & 2
G: ESC signal ground
Voltage meter scale: 1100
Current Sensor: 104A (Scale 317)

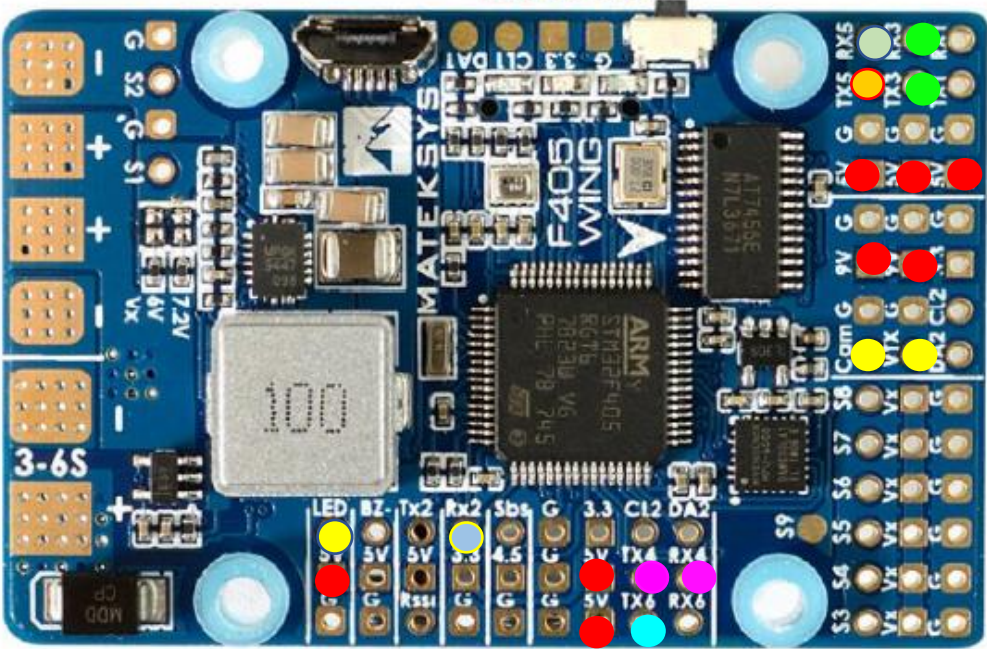
Button: Boot(DFU) mode button
LED0(Blue) & LED1(Green): FC Status indicator
LED2(Red):3.3V indicator
[DA1 CL1] : I2C1, supports Baro only. BMP280 /MS5611 /BMP085

LED2 LED1 LED0

ESC1

ESC2

BAT



MCU: STM32F405RGT6(168MHz)
IMU: MPU6000
OSD: INAV OSD
Baro: BMP280
BlackBox: MicroSD Slot

16.1.2021/28.6.2024
DUPE

Sbs: Built in inverter of RX2 for SBUS input
RX2: UART2-RX for DSM2, DSMX, IBUS, PPM share RX2 pad
TX2: Softserial_TX1 w/ CPU based serial ports enabled
TX2: UART2-TX pin w/o Softserial enabled
TX4/RX4: UART4
TX6/RX6: UART6

5V: onboard BEC 5V 2A cont. Max.3A
4V5: 4.4~4.8V, the voltage is also supplied when connecting via USB
3.3: LDO3.3V Max.500mA
G: Ground

LED: WS2812 LED signal output
Bz- & 5V: General active 5V buzzer
Bz-, 5V & G: Matek Dbuz5V
Rssi: Frsky RSSI input

TX1/RX1: UART1
TX3/RX3: UART3
TX5/RX5: UART5
5V: onboard BEC 5V 2A cont. Max.3A
G: Ground

VTX: Video Transmitter Signal
Cam: Camera video signal
9V: onboard BEC 9V 2A cont. Max.3A,
12V option w/ 12V jumper bridged.

[DA2 CL2] : I2C2, for compass and Pitot
compass HMC5883 /MAG3110 /QMC5883 /IST8310
Pitot_MS4525

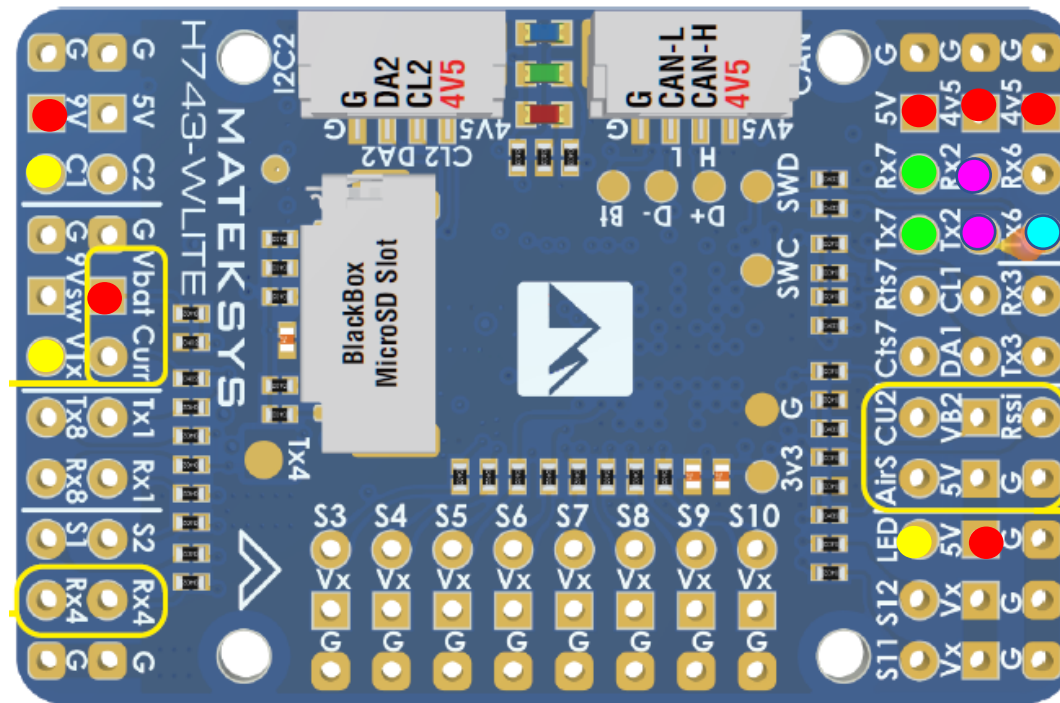
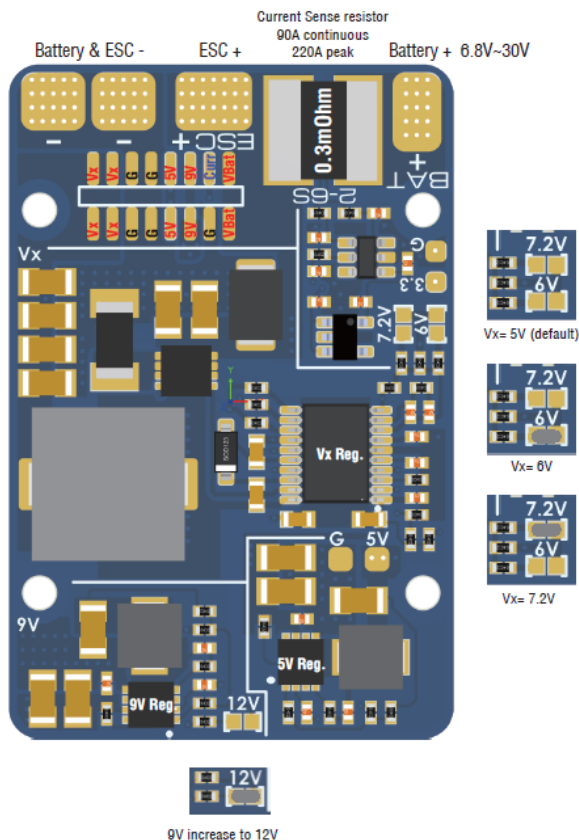
S3/S4/S5/S6/S7/S8/S9: Servo signal
Vx: onboard BEC 5V/6V/7.2V 5A cont. Max.6A
for servos, Default is 5V

UART1	
UART2	ESC TELEMETRY (RX2)
UART3	LTM 9600 - TELEMETRY LORA
UART4	GPS MODUL -
UART5	TRAMP MENU (TX5)
UART6	SRXL2 REC (TX6) SPEKTRUM 4650

AUX:
CH5 (C) – NO / ARM / ARM
CH6 (D) – MANUAL / RATE / HORIZON
CH7 (F) – NO / NAV CRUISE / NAV RTH
CH8 (B) – NO / ALTHOLD / NAV LOITER

MATEK F405SE + iNAV MATEKF405SE

- MCU: STM32F405
- IMU: MPU6000 accelerometer/gyro (SPI)
- Baro: BMP280 (I2C)
- OSD: INAV OSD w/ AT7456E chip
- Blackbox: MicroSD card slot (SD/SDHC)
- VCP & 6x UARTs
- 2x Motors, 7x Servos outputs, 2x I2C
- 3x LEDs for FC STATUS (Blue, Red) and 3.3V indicator(Red)
- Built in inverter for SBUS input (UART2-RX)
- PPM/UART Shared: UART2-RX
- SoftSerial on TX2 pad
- Battery Voltage Sensor: 1:10 (Scale 1100)
- WS2812 Led Strip : Yes
- Beeper : Yes , RSSI: Yes
- Mounting: 30.5 x 30.5mm, Φ4mm with Grommets Φ3mm
- Dimensions: 56 x 36 x 13 mm Weight: 25g



UART1	
UART2	GPS MODUL BN-220
UART3	
UART4	ESC Telemetry (Rx)
UART6	SRXL2 REC (TX6) - SPEKTRUM 4650
UART7	9600 LTM TELEMETRY LORA E32-TTL

MATEK H743 WHITE

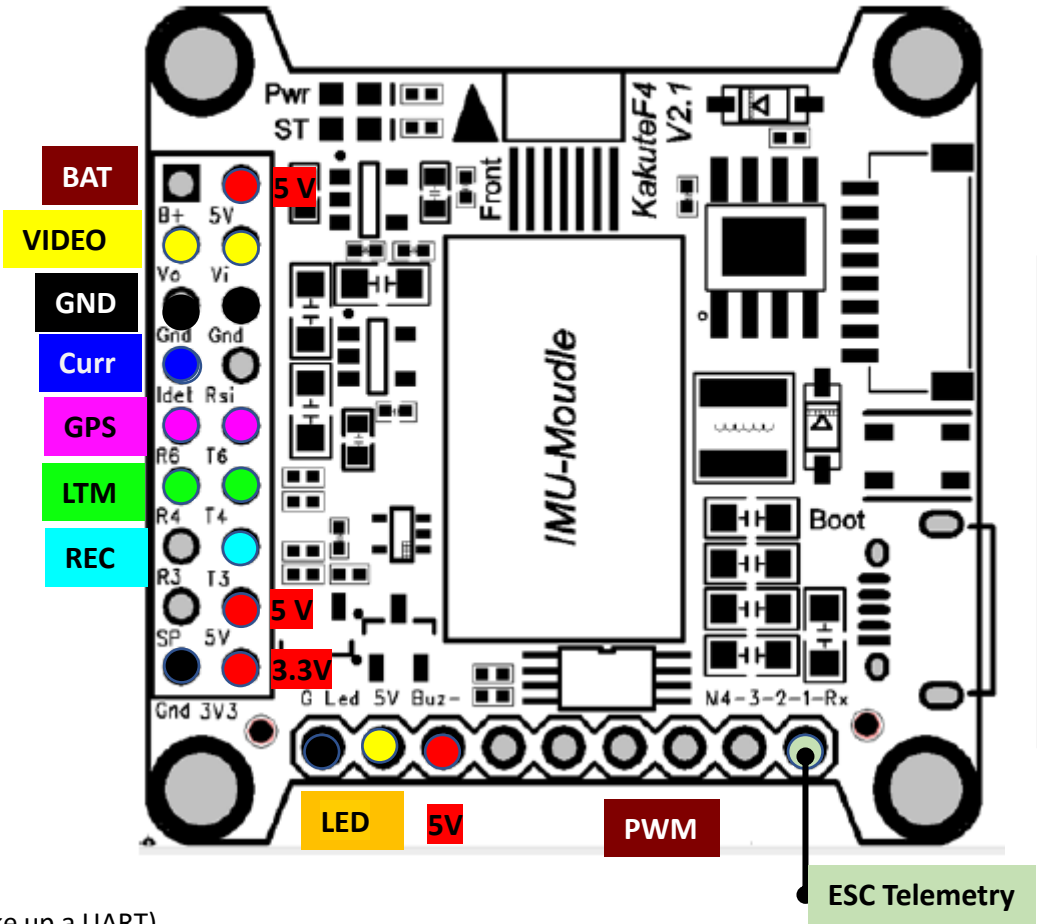
CPU: STM32H743VIH6, 480MHz, 2MB Flash
IMU: ICM42688-P (SPI1)
Baro: DPS310 (I2C2)
OSD: AT7456E (SPI2)
Blackbox: MicroSD card slot (SDIO)
7x Uarts (1,2,3,4,6,7,8) with built-in inversion
13x PWM outputs
2x I2C
1x CAN
6x ADC (VBAT, Current, RSSI, Analog AirSpeed, VB2, CU2)
1x JST-GH_4pin connector for I2C2
1x JST-GH_4pin connector for CAN
1x JST-SH_6pin connector for external USB and buzzer
Dual Camera Inputs switch
9V(12V) for VTX power switch
6.8~30V DC IN (2~6S LiPo)
High-precision Current Sense 220A Range
BEC 5V 2A for FC
BEC 9V 2A for camera/VTX, 12V option
BEC Vx 8A cont. 10A Peak for servos, 5V, 6V or 7.2V option
LDO 3.3V 200mA
INAV Target: MATEKH743
4V5: 4.4~4.8V, Max.500mA
5V: onboard BEC 5V 2A cont. Max.3A
9V: 9V output, 9V will increase to 12V if "12V"
Vbat: Battery voltage
onboard battery voltage sense: INAV scale 2100
Curr: Current signal (0~3.3V)
onboard current sense: INAV scale 150
CU2: for external current sensor, 0~3.3V

Top of board

UART1	
UART2	
UART3	SRXL2 REC (TX3) - SPEKTRUM 4650
UART4	9600 LTM TELEMETRY LORA
UART5	ESC Telemetry (R5)
UART6	GPS MODUL (TX6+RX6) BN-220

Holybro Kakute F4 V2 + iNAV KAKUTEF4V2

- MCU: STM32F405RGT6 32-bit processor
- IMU: ICM20689 (SPI)
- Barometer: BMP280
- USB VCP Driver (all UARTs usable simultaneously; USB does not take up a UART)
- 5 hardware UARTS (UART1,3,4, 5, 6)
- Supports serial receivers (SBUS, iBus, Spektrum, Crossfire) only.
- PPM and PWM receivers are not supported.
- 128 Mbit Dataflash chip for Blackbox logging
- Dimensions: 35x30x8mm (includes USB in height)
- Mounting Holes: Standard 30.5mm square to center of holes
- Weight: 7g



Pin	Function
1	Battery Voltage
2	R5 (for ESC telemetry)
3	Ground
4	Current Sensor Input
5	M1
6	M2
7	M3
8	M4

Pin	Function
Buz-	Piezo buzzer negative leg
Led	WS2812 addressable LED signal wire
SP	FrSky SmartPort Telemetry (UART 1, inverted)
R3, T3	UART3 RX and TX (automatic inversion)
R4, T4	UART4 RX and TX (uninverted)
R6, T6	UART6 RX and TX (uninverted)
Rsi	Analog (0-3.3v) RSSI input
Idet	Current Sensor (0-3.3v) input
3V3	3.3v output (200 mA max)
5v	5v output (1.5 A max)
M1 to M4	Motor signal outputs
RX	UART 5 RX (uninverted, for ESC Telemetry)
VO	Video output to video transmitter
VI	Video input from FPV camera
Boot	Bootloader button
G or Gnd	Ground
B+	Battery positive voltage (2S-6S)

AIRBOT OMNIBUS F4Pro + iNAV OMNIBUSF4PRO

- STM32 F405 MCU
- SPI Gyro MPU6000
- On-Board OSD (FC over SPI bus)
- Baro (BMP280)
- MicroSD Blackbox
- 5v3a SBEC
- 6PWM output
- Built-in Current Sensor
- On-Board Video Filter 5V to VTX and Camera

VTX TRAMP (2S-4S)
CAMERA (5-40V)

iNAV
OMNIBUSF4Pro

BETAFLIGHT
OMNIBUSF4Pro

PWM1 B00 - MOTOR1
PWM2 B01 - MOTOR2
PWM3 A03 - PITCH/ELEV
PWM4 A02 - ROLL/AIL1
PWM5 A01 - ROLL/AIL2
PWM6 A08 - YAW/RUDD

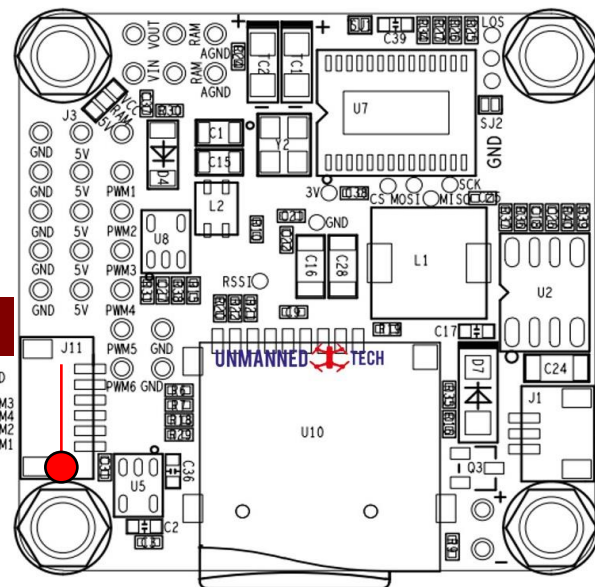
resource MOTOR 1 B00
resource MOTOR 2 B01
resource MOTOR 3 NONE
resource MOTOR 4 NONE
resource SERVO 1 A03
resource SERVO 2 A02
resource SERVO 3 A01
resource SERVO 4 A08

B00: MOTOR1
B01: MOTOR2
A03: MOTOR3
A02: MOTOR4
A01: MOTOR5
A08: MOTOR6

mixer CUSTOMAIRPLANE
smix reset
smix 0 3 0 100 0
smix 1 4 0 100 0
smix 2 5 2 100 0
smix 3 2 1 100 0

smix 0 3 0 100 0 -1
smix 1 4 0 100 0 -1
smix 2 3 14 100 0 -1
smix 3 4 14 -100 0 -1
smix 4 5 2 100 0 -1
smix 5 2 1 100 0 -1

set platform_type = AIRPLANE
mmix 0 1.000 0.000 0.000 0.000
mmix 1 1.000 0.000 0.000 0.000



BAT

ESC

REC

LED

Omnibus
F4Pro(V3)

3.3V

5V

LTM

GPS

UART	
UART1	SRXL2 REC (TX1) SPEKTRUM 4650
UART2	
UART3	GPS MODUL (TX3+RX3) BN-220
UART4	
UART5	
UART6	9600 LTM TELEMETRY LORA (TX6+RX6) E32-TTL

28.01. 2020
DuPe

SucceX-E F4 V2.1 Flight Controller + BTFL IFLIGHT_SUCCEX-E F4

- MCU : STM32F405
- Gyro : MPU6000
- Baro: BMP280(I2C)
- Betaflight OSD : IFLIGHT OSD (AT7456E)
- Blackbox : 16MB(W25Q128)
- 4X Uarts
- 4 x Dshot/Proshot/Oneshot output
- 4x0201 LEDs for FC STATUS (Blue, Red, Orange)
- 3.3V indicator(Red) BAT/+5V/3.3V/start
- 1 x Group of Gnd/Vbat/M1/M2/M3/M4/Cur/TX
- VTX telemetry: YES
- WS2812 led Strip : YES
- Beeper : YES
- Input : 2-6S (Max 8S)
- BEC : 5V / 3A
- **Firmware target : IFLIGHT_SUCCEX-E F4**
- Mounting : 30.5*30.5/φ4
- Dimensions : 36*36mm
- Weight : 6.9g

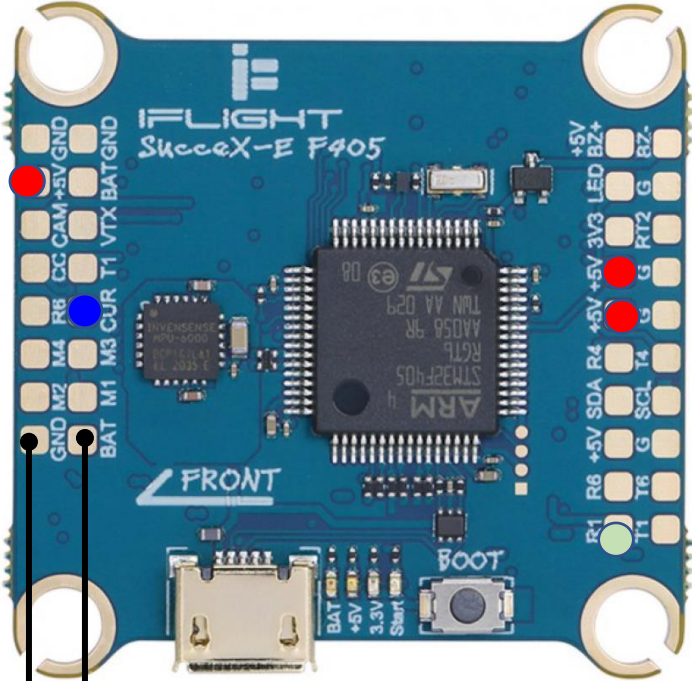
UART1	ESC TELEMETRY (RX1) / TRAMP MENU (TX1)
UART2	9600 LTM TELEMETRY LORA (TX2+RX2) E32-TTL
UART3	
UART4	GPS MODUL (TX4+RX4) BN-220
UART5	
UART6	

BTFL

resource MOTOR 1 B00
resource MOTOR 2 B01
resource MOTOR 3 NONE
resource MOTOR 4 NONE
resource SERVO 1 C09
resource SERVO 2 C08
mixer AIRPLANE

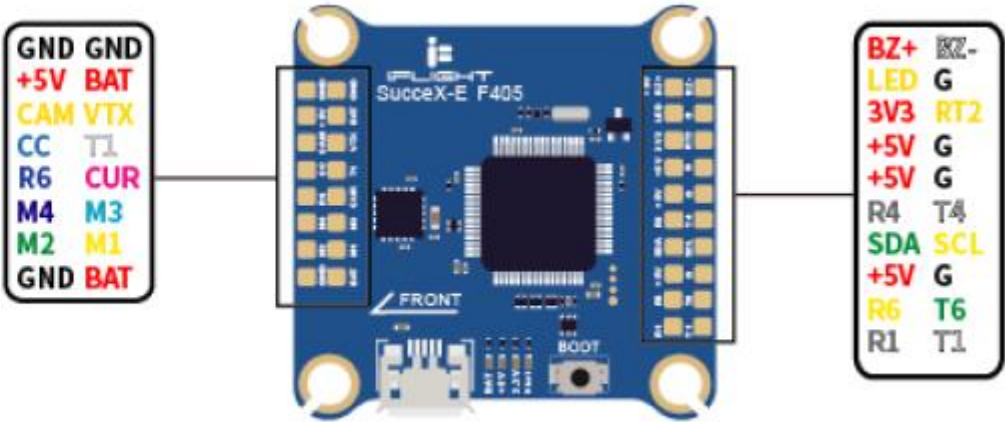
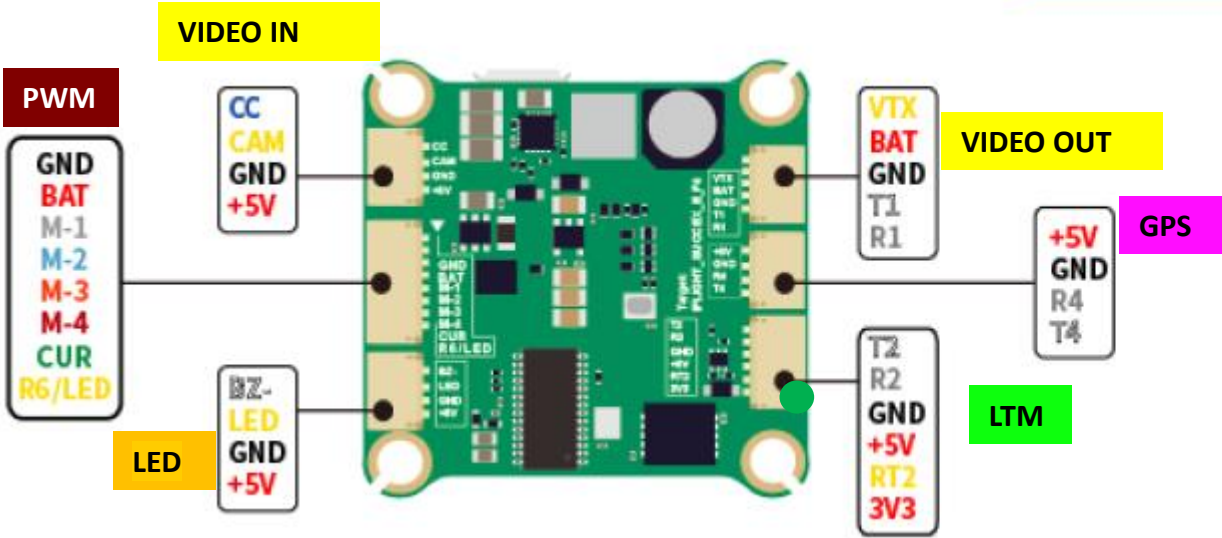
INAV MIX

S1 MOTOR1
S2 MOTOR2
S3 PITCH/ELEV
S4 ROLL/AIL1
S5/S6 - NO



BAT

inav_3.0.0_IFLIGHT_SUCCEX_E_F4_21.hex
(iFlight SucceX-iNavFlight/inav-configurator · GitHub)



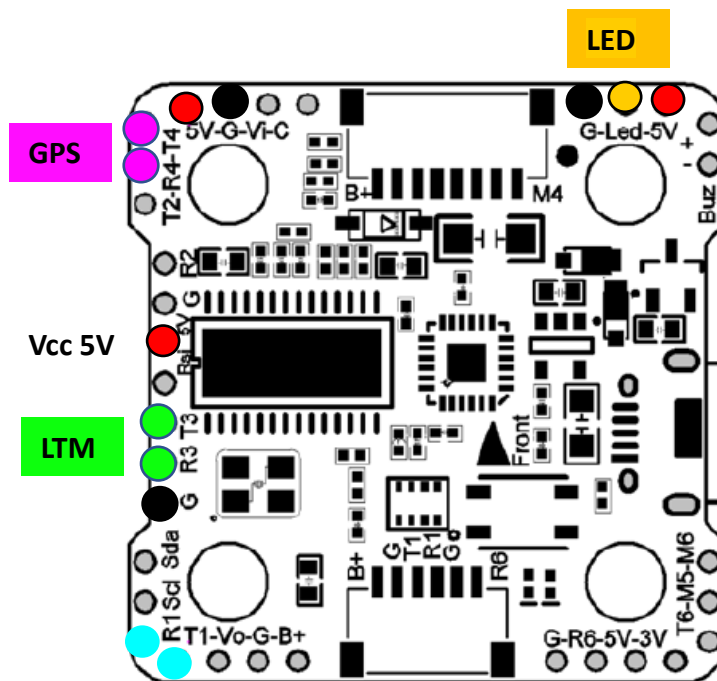
Holybro Kakute F7 Mini V3 + BTFL KAKUTEF7MINIV3

- MCU: STM32F722RET6 32-bit processor, 216MHz, 256Kbytes RAM, 512Kbytes Flash
- IMU: MPU6000 (SPI)
- Barometer: BMP280
- USB VCP Driver (all UARTs usable simultaneously; USB does not take up a UART)
- 5 hardware UARTS (UART1, 2, 3, 4, 6)
- Supports serial receivers (SBUS, iBus, Spektrum, Crossfire) only.
- PPM and PWM receivers are not supported.
- Onboard 16Mbytes for Blackbox logging
- 5V Power Out: 1.0A max
- 3.3V Power Out: 0.2A max
- Dimensions: 30x30mm
- Mounting Holes: Standard 20mm square to center of holes (M4)
- Weight: 4g

UART2	
UART3	9600 LTM TELEMETRY LORA (TX3+RX3) E32-TTL
UART4	GPS MODUL (TX4+RX4) BN-220
UART5	
UART6	

31.8.2021
DuPe

Pin1	Battery positive voltage (2S-6S)
Pin2	R4 (for ESC telemetry)
Pin3	Ground
Pin4	Current Sensor Input
Pin5	M1
Pin6	M2
Pin7	M3
Pin8	M4



Pin1	Battery positive voltage (2S-6S)
Pin2	Ground
Pin3	T1
Pin4	R1
Pin5	Ground
Pin6	R6

Pin	Function
C	To camera OSD control
5v	5v output (1.0A max)
VO	Video output to video transmitter
VI	Video input from FPV camera
G	Ground
SDA, SCL	I ² C connection (for peripherals)
R1, T1	UART1 RX and TX
R2, T2	UART2 RX and TX
R3, T3	UART3 RX and TX
R4, T4	UART4 RX and TX
R6, T6	UART6 RX and TX
LED	WS2812 addressable LED signal wire
Buz-	Piezo buzzer negative leg
Buz+	Connect buzzer positive leg to 5v pad
3V3	3.3v output (200 mA max)
M5, M6	Additional motor signal outputs (located at side of board)
Rssi	Analog RSSI (0-3.3v) input from receiver
B+	Battery positive voltage (2S-6S)
Boot	Bootloader button

AIRBOT OMNIBUS F4V6 + iNAV OMNIBUSF4V6

27.1.2020

DuPe

- STM32 F405 MCU
- INCL. BARO BMP280
- SPI Sensor MPU6000
- 6PWM output, 5x UART
- V1A BEC on board(3-6s) 8V BEC Camera
- FlashOnly 36x36mm,
- holes 30.5x30.5mm

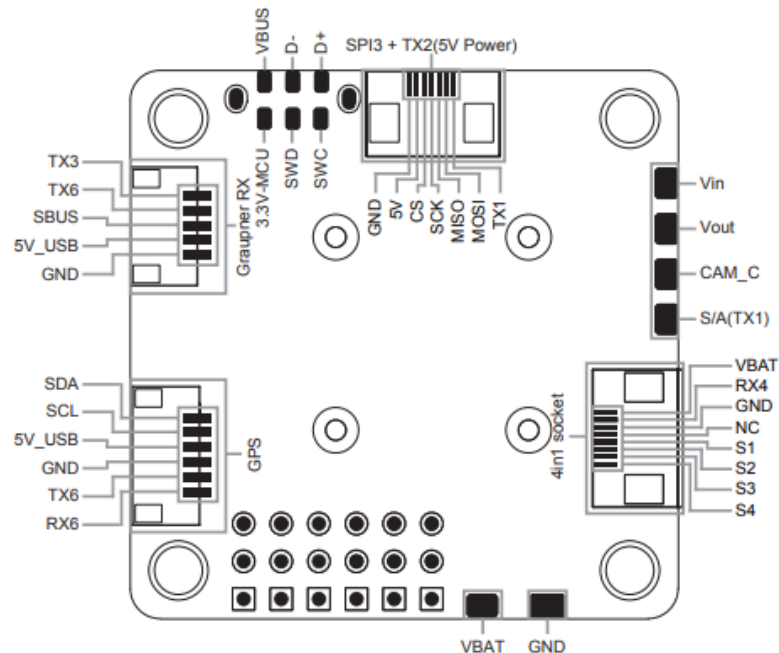
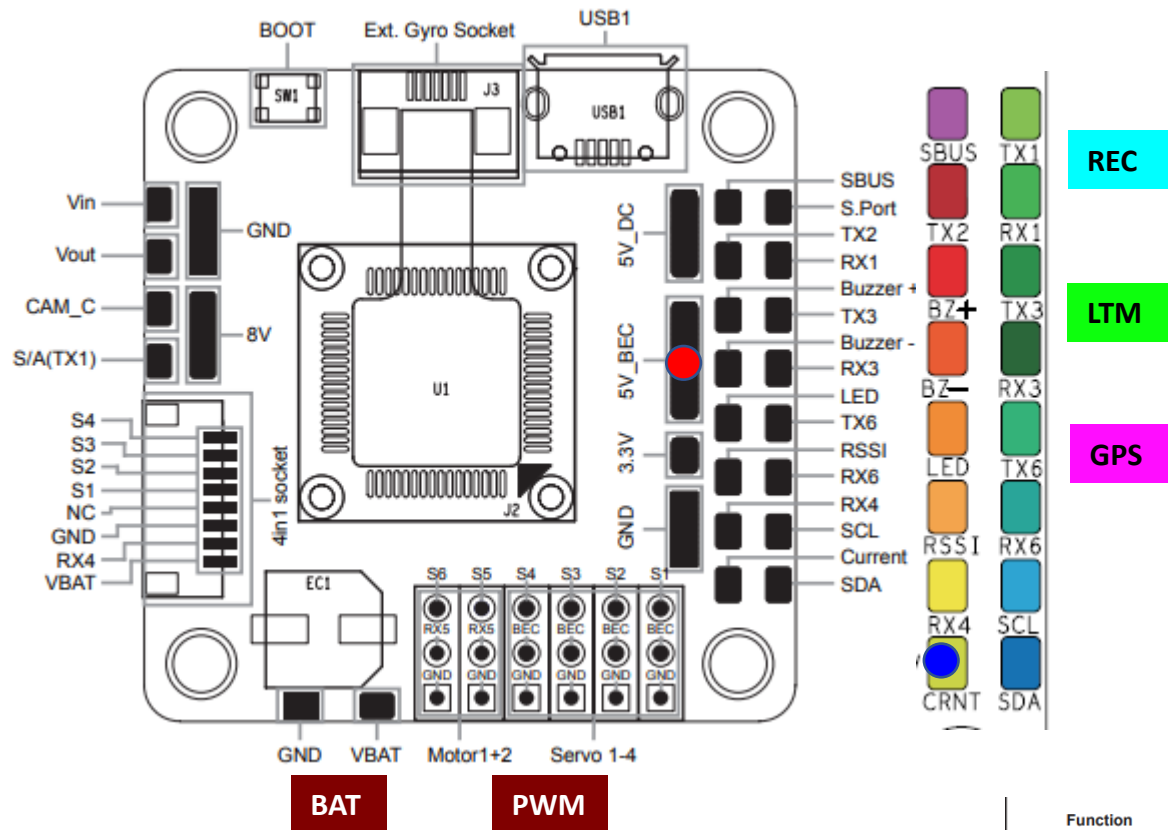
iNAV - OMNIBUSF4V6

S1 B00 - MOTOR1
S2 B01 - MOTOR2
S3 A03 - PITCH/ELEV
S4 B05 - ROLL/AIL1
S5 C09 - YAW/RUDD
S6 C08 - ROLL/AIL2

smix 0 3 0 100 0 -1
smix 1 4 0 100 0 -1
smix 2 3 14 100 0 -1
smix 3 4 14 -100 0 -1
smix 4 5 2 100 0 -1
smix 5 2 1 100 0 -1

set platform_type = AIRPLANE
mmix reset
mmix 0 1.000 0.000 0.000 0.000
mmix 1 1.000 0.000 0.000 0.000

UART1	SRXL2 REC (TX1) SPEKTRUM 4650
UART2	
UART3	9600 LTM TELEMETRY LORA (TX3+RX3) E32-TTL
UART4	
UART5	
UART6	GPS MODUL (TX6+RX6) BN-220



BTFL - OMNIBUSF4V6

resource MOTOR 1 C08
resource MOTOR 2 C09
resource SERVO 1 B05
resource SERVO 2 A03
resource SERVO 3 B01
resource SERVO 4 B00

mixer CUSTOMAIRPLANE

smix reset
smix 0 3 0 100 0 0 100 0
smix 1 4 0 100 0 0 100 0
smix 2 2 1 100 0 0 100 0
smix 3 5 2 100 0 0 100 0

Function	Solder Pad Silk screen	Resources	MCU Pin	Notes
SBUS	RC	UART1	PA10	Build-in inverter
DSM2	TX1	UART1	PA9	CLI serialrx_halfduplex set to ON
Smart Audio VTX	S/A	UART2	PA2	
Smartport	TX1	Software serial	PA9	Invalid when using DSM2 RX
ESC Telemetry	RX4	UART4	PA1	
Camera Control	CAM_C		PB9	
IIC2_SDA	RX3	UART3	PB11	
IIC2_SCL	TX3	UART3	PB10	
GPS	RX6/TX6	UART6	PC7/PC6	
WS2812B LED	LED		PB6	
Buzzer	Bz-/Bz+		PB4	
Current sensor scale				175
Current sensor offset				-19700 (±2000)
Current range				default 150A extended by sample resistor up to 320A

Note: not all combinations are valid. When the flight controller firmware detects this the serial port configuration will be reset.

Note: Do **NOT** disable MSP on the first serial port unless you know what you are doing. You may have to reflash and erase your configuration if you do.

Identifier	Data	Telemetry	RX	Sensors	Peripherals
USB VCP	☒ MSP 115200 ▾	Disabled ▾ AUTO ▾	☐ Serial RX	Disabled ▾ 115200 ▾	Disabled ▾ 115200 ▾
UART1	☒ MSP 9600 ▾	LTM ▾ 9600 ▾	☐ Serial RX	Disabled ▾ 115200 ▾	Disabled ▾ 115200 ▾
UART2	☐ MSP 115200 ▾	Disabled ▾ AUTO ▾	☐ Serial RX	Disabled ▾ 115200 ▾	Disabled ▾ 115200 ▾
UART3	☐ MSP 115200 ▾	Disabled ▾ AUTO ▾	☐ Serial RX	Disabled ▾ 115200 ▾	Disabled ▾ 115200 ▾
UART4	☐ MSP 115200 ▾	Disabled ▾ AUTO ▾	☐ Serial RX	GPS ▾ 115200 ▾	Disabled ▾ 115200 ▾
UART5	☐ MSP 115200 ▾	Disabled ▾ AUTO ▾	☐ Serial RX	Disabled ▾ 115200 ▾	Disabled ▾ 115200 ▾
UART6	☐ MSP 115200 ▾	Disabled ▾ AUTO ▾	☒ Serial RX	Disabled ▾ 115200 ▾	Disabled ▾ 115200 ▾
SOFTSERIAL1	☐ MSP 115200 ▾	Disabled ▾ AUTO ▾	☐ Serial RX	Disabled ▾ 115200 ▾	Disabled ▾ 115200 ▾

INAV Configurator

INAV

CONFIGURATOR 3.0.1

FC FIRMWARE 3.0.1

2021-07-27 @ 19:18:47 -- Unique device ID received - 0x2200514d4b500f20353252

Show Log

Calibration

Mixer

Outputs

Presets

Ports

Configuration

Failsafe

PID tuning

Advanced Tuning

Programming

Receiver

Modes

Adjustments

GPS

Mission Control

OSD

LED Strip

Sensors

Tethered Logging

Blackbox

CLI

11.71 V

Gyro Accel Mag Baro GPS Flow Sonar Speed

No dataflash chip found

Profile 1 Battery profile 1 Disconnect

Receiver

DOCUMENTATION

Please read receiver chapter of the documentation. Configure serial port (if required), receiver mode (serial/ppm/pwm), provider (for serial receivers), bind receiver, set channel map, configure channel endpoints/range on TX so that all channels go from ~1000 to ~2000. Set midpoint (default 1500), trim channels to 1500, configure stick deadband, verify behaviour when TX is off or out of range. Make sure that the channel values all increase when you push the sticks up and to the right. If not, reverse the channel in the TX. Do not apply any other mixing in the TX.

IMPORTANT: Before flying read failsafe chapter of documentation and configure failsafe.

Channel Map

RSSI Channel

TAER Disabled

Roll [A] 1560

Pitch [E] 1454

Yaw [R] 1512

Throttle [T] 1159

CH 5 1841

CH 6 1841

CH 7 1841

CH 8 1841

CH 9 1500

CH 10 1500

CH 11 1500

CH 12 1500

CH 13 1500

CH 14 1500

CH 15 1500

CH 16 1500

CH 17 1500

CH 18 1500

Receiver Mode

SERIAL Receiver type

Note: Remember to configure a Serial Port (via Ports tab) for the serial receiver

SRXL2 Serial Receiver Provider

OFF Serial Port Inverted (comparing to protocol default)

OFF Serial receiver half-duplex

Throttle MID 0,50

Throttle EXPO 0,00

RC Deadband 5

Yaw Deadband 5

RC Expo 0,30

Manual RC Expo 0,70

RC Yaw Expo

Manual RC Yaw Expo

Save and Reboot