

ArduCopter Mission Planner PID usage Map 4 9/1/2012

ArduCopter Pid = default value	Arducopter Config	Parameter List
Angular Rate Control P = .175	Rate Pitch / Rate Roll	RATE_PIT / RATE_RLL
Angular Rate Control I = 0.0		
Angular Rate Control D = 0.004		
Angular Rate Control IMAX = 5		
Dampening Dampen = 0.0	Stabilize D	STAB_D
Dampening Dynamic = 0.5	-----	STAB_D_S
Stabilize Control P = 4.5	Stabilize Pitch / Stabilize Roll	STB_PIT / STB_RLL
Stabilize Control I = 0.05		
Stabilize Control IMAX = 8		
Yaw Angular Rate Cont P = .25	Rate Yaw	RATE_YAW
Yaw Angular Rate Cont I = 0.02		
Yaw Angular Rate Cont D = 0.0		
Yaw Angular Rate Cont IMAX = 8		
Yaw Stabilize Control P = 7	Stabilize Yaw	STB_YAW
Yaw Stabilize Control I = 0.02		
Yaw Stabilize Control IMAX = 8		
Loiter Angular Rate Cont P = 2.4	Rate Loiter	LOITER_LAT / LOITER_LON
Loiter Angular Rate Cont I = 0.08		
Loiter Angular Rate Cont D = 0.4		
Loiter Angular Rate Cont IMAX=30		
Loiter Speed P = 0.2	Loiter P	HLD_LAT / HLD_LON
-----	Loiter I = 0.0	
-----	Loiter IMAX = 30	
WP Nav Rate Cont P = 2.4	Nav WP	NAV_LAT / NAV_LON
WP Nav Rate Cont I = 0.17		
WP Nav Rate Cont D = 0.0		
WP Nav Rate Cont IMAX = 18		
WP Speed m/s = 5	m/s	WP_SPEED_MAX
Altitude Hold Error P = 0.3	Altitude Hold	THR_ALT
Altitude Hold Error I = 0.04		
Altitude Hold Error IMAX = 3		
Alt Hold Thrust Rate P = 0.3	Throttle Rate	THR_RATE
Alt Hold Thrust Rate I = 0.03		
Alt Hold Thrust Rate D = 0.0		
Alt Hold Thrust Rate IMAX = 0		