

Operation manual for BLHeli SiLabs Rev14.x

BLHeli firmware is designed for use in brushless ESCs in helicopters, multirotors, planes and more.

The firmware supports a multitude of ESC hardware.

There are three versions of the code:

- Main: Intended for helicopter main motor, and supports:
 - Soft spoolup
 - Governor
 - Low voltage limiting
- Tail: Intended for helicopter tail motor, and supports:
 - Rapid throttle response
 - Idling (the motor runs a few seconds after throttle is zeroed, in order to avoid stops in the air)
 - Bidirectional operation
- Multi: Intended for multirotor motors, and supports:
 - Rapid throttle response
 - Closed loop operation
 - Bidirectional operation

All codes run the motor smoothly and with good throttle linearity.

All codes support a damped light mode (on hardware that support it).

Damped light does braking, causing very fast motor retardation, and inherently also does active freewheeling.

All codes support features to prevent sync loss. This is mostly required in multirotor applications. There are tuneable parameters that can make the code run well with almost any motor.

All codes support 1kHz, 2kHz, 4kHz, 8kHz and 12kHz PWM input signal in environments where the ESC takes its input from a source that would normally drive a brushed motor. The code also supports regular 1-2ms pulse width PPM input or OneShot125 (125-250us), at a rate up to almost 4kHz. The input signal is automatically detected by the ESC upon power up.

All codes support a beacon functionality, where the ESC will start beeping after a given time of zero throttle. This can be very useful for finding lost crafts.

Programming functions and parameter values:

Programming parameter value table main:

Function	1	2	3	4	5	6	7	8	9	10	11	12	13
1 - Governor P gain	0.13	0.17	0.25	0.38	0.50	0.75	1.00	1.5	2.0	3.0	4.0	6.0	8.0
2 - Governor I gain	0.13	0.17	0.25	0.38	0.50	0.75	1.00	1.5	2.0	3.0	4.0	6.0	8.0
3 - Governor mode	Tx	Arm*	Setup	Off	-	-	-	-	-	-	-	-	-
4 - Governor range	High	Middle	Low	-	-	-	-	-	-	-	-	-	-
5 - Low voltage limit (/cell)	Off	3.0V	3.1V	3.2V	3.3V	3.4V	-	-	-	-	-	-	-
6 - Startup power**	0.031	0.047	0.063	0.094	0.125	0.188	0.25	0.38	0.50	0.75	1.00	1.25	1.50
7 - Commutation timing	Low	MediumLow	Medium	MediumHigh	High	-	-	-	-	-	-	-	-
8 - Pwm frequency	High	Low	DampedLight	-	-	-	-	-	-	-	-	-	-
9 - Demag compensation	Off	Low	High	-	-	-	-	-	-	-	-	-	-
10 - Rotation direction	Normal	Reversed	-	-	-	-	-	-	-	-	-	-	-
11 - Input pwm polarity	Positive	Negative	-	-	-	-	-	-	-	-	-	-	-

*: Governor arm mode is only supported with PWM input signal

** : Default startup power varies by ESC. Generally the default power is lower for larger ESCs.

Default values are marked in bold **green**.

If for some reason there is an error in the eeprom/flash write operation (e.g. due to loss of power or low voltage), defaults will be loaded.

Programming parameter value table tail:

Function	1	2	3	4	5	6	7	8	9	10	11	12	13
1 - Tail gain	0.75	0.88	1.00	1.12	1.25	-	-	-	-	-	-	-	-
2 - Tail idle speed	Low	MediumLow	Medium	MediumHigh	High	-	-	-	-	-	-	-	-
3 - Startup power**	0.031	0.047	0.063	0.094	0.125	0.188	0.25	0.38	0.50	0.75	1.00	1.25	1.50
4 - Commutation timing	Low	MediumLow	Medium	MediumHigh	High	-	-	-	-	-	-	-	-
5 - Pwm frequency	High	Low	DampedLight*	-	-	-	-	-	-	-	-	-	-
6 - Pwm dither***	Off	3	7	15	31	-	-	-	-	-	-	-	-
7 - Demag compensation	Off	Low	High	-	-	-	-	-	-	-	-	-	-
8 - Rotation direction	Normal	Reversed	Bidirectional	-	-	-	-	-	-	-	-	-	-
9 - Input pwm polarity	Positive	Negative	-	-	-	-	-	-	-	-	-	-	-

*: Only enabled for some ESCs.

** : Default startup power varies by ESC. Generally the default power is lower for larger ESCs.

***: For code revs 14.4 and before, dither range was 7/15/31/63.

Default values are marked in bold **green**.

If for some reason there is an error in the eeprom/flash write operation (e.g. due to loss of power or low voltage), defaults will be loaded.

Programming parameter value table multi:

Function	1	2	3	4	5	6	7	8	9	10	11	12	13
1 - Closed loop P gain	0.13	0.17	0.25	0.38	0.50	0.75	1.00	1.5	2.0	3.0	4.0	6.0	8.0
2 - Closed loop I gain	0.13	0.17	0.25	0.38	0.50	0.75	1.00	1.5	2.0	3.0	4.0	6.0	8.0
3 - Closed loop mode	HiRange	MidRange	LoRange	Off	-	-	-	-	-	-	-	-	-
4 - Multi gain	0.75	0.88	1.00	1.12	1.25	-	-	-	-	-	-	-	-
5 - Startup power**	0.031	0.047	0.063	0.094	0.125	0.188	0.25	0.38	0.50	0.75	1.00	1.25	1.50
6 - Commutation timing	Low	MediumLow	Medium	MediumHigh	High	-	-	-	-	-	-	-	-
7 - Pwm frequency	High	Low	DampedLight*	-	-	-	-	-	-	-	-	-	-
8 - Pwm dither***	Off	3	7	15	31	-	-	-	-	-	-	-	-
9 - Demag compensation	Off	Low	High	-	-	-	-	-	-	-	-	-	-
10 - Rotation direction	Normal	Reversed	Bidirectional	-	-	-	-	-	-	-	-	-	-
11 - Input pwm polarity	Positive	Negative	-	-	-	-	-	-	-	-	-	-	-

*: Only enabled for some ESCs. From code rev 14.4, damped light is default on the ESCs that support it. For prior code revisions, high is default.

** : Default startup power varies by ESC. Generally the default power is lower for larger ESCs.

***: For code revs 14.4 and before, dither range was 7/15/31/63.

Default values are marked in bold **green**.

If for some reason there is an error in the eeprom/flash write operation (e.g. due to loss of power or low voltage), defaults will be loaded.

Programming parameters for main:

In the governor “tx” mode, the throttle value while running sets the speed target for the governor.
In this mode, the throttle curve when flying should be flat.

In the governor “arm” mode the maximum throttle seen during the arming sequence will set the speed target for the governor.
Note that governor “arm” mode is not supported for PPM input signal.

In the governor “setup” mode the governor target is stored in the ESC. It’s default value is 70% (about 4800rpm on mCPX with a 6pole motor and an 8T pinion). The value can be changed with configuration software.

In governor “arm” and “setup” modes, the throttle curve when flying does not influence headspeed.
Throttle curve can be set to a V-curve for the desired main to tail mix (this mix is in the mCPX 3in1).
Throttle must be above 20% in these modes. Values below 20% will cause spooldown.

Governor P gain sets the proportional gain for the governor.
This setting controls the gain from speed error to motor power.

Governor I gain sets the integral gain for the governor.
This setting controls the gain from integrated speed error (summed over time) to motor power.

Governor range sets the available range of speeds that the governor can operate on.

- For the high range, throttle values from 25% to 100% will lead to governor targets from 70000 to 208000 electrical rpm
 - For the middle range, throttle values from 25% to 100% will lead to governor targets from 39000 to 156000 electrical rpm
 - For the low range, throttle values from 25% to 100% will lead to governor targets from 20000 to 89000 electrical rpm
- The low range is primarily intended for low pole count motors (e.g. 2-pole inrunners).

The low voltage limit sets the voltage at which motor power is reduced.
Motor power is reduced while at this voltage, but only temporarily, and full power is resumed if the voltage rises again.
Low voltage limiting can also be disabled.

Programming parameters for multi:

In the closed loop mode, the throttle value while running sets the rpm target of the motor.

Closed loop P gain sets the proportional gain for the rpm control loop.
This setting controls the gain from speed error to motor power.

Closed loop I gain sets the integral gain for the rpm control loop.
This setting controls the gain from integrated speed error (summed over time) to motor power.

Closed loop mode sets the range of speeds that the control loop can operate on.

- For the high range, throttle values from 0% to 100% linearly correspond to rpm targets from 0 to 200000 electrical rpm
- For the middle range, throttle values from 0% to 100% linearly correspond to rpm targets from 0 to 100000 electrical rpm
- For the low range, throttle values from 0% to 100% linearly correspond to rpm targets from 0 to 50000 electrical rpm

When closed loop mode is set to off, the control loop is disabled.

Programming parameters for tail/multi:

Tail/multi gain scales the power applied to the motor for a given input. Note that this is only for PWM input, for PPM input it has no effect.
Beware that a low tail/multi gain will also limit the maximum power to the motor.

Tail idle speed is the speed of the motor during the delayed stop.

Rotation direction can be set to "bidirectional" for tail and multi codes.

In this mode, center throttle is zero and above is fwd rotation and below is reverse rotation.

Bidirectional operation is only supported for PPM input signal.

When bidirectional operation is selected, programming by TX is disabled.

Direction change performance can be somewhat controlled by startup power. Higher startup power can give faster reversal, but at some point it can also lead to motor occasionally stalling.

Pwm dither is a parameter that adds some variation to the motor pwm off cycle length. This can reduce problems (like throttle steps or vibration) in rpm regions where the pwm frequency is equal to harmonics of the motor commutation frequency, and it can reduce the step to full throttle. It is primarily beneficial when running damped light mode. Dither is not applied in closed loop mode.

Programming parameters for main/tail/multi:

Startup is always done with the direct startup method, which runs the motor using back emf detection from the very start. In this mode power is given by the throttle used, but limited to a maximum level (and from rev14.5 to a minimum level that is a quarter of the maximum level). This maximum level can be controlled with the startup power parameter. Beware that setting startup power too high can cause excessive loading on ESC or motor!

For low rpms, the maximum power to the motor is limited, in order to facilitate detection of low BEMF voltages. The maximum power allowed can be set via the startup power parameter. A lower startup power parameter will give lower maximum power for low rpms (this is implemented from rev14.6).

Commutation timing can be adjusted in three steps. Low is about 0° , mediumlow 8° , medium 15° , mediumhigh 23° and high 30° .

Typically a medium setting will work fine, but if the motor stutters it can be beneficial to change timing.

Some motors with high inductance can have a very long commutation demagnetization time. This results in motor stop or stutter upon quick throttle increase, particularly when running at a low rpm. Setting timing to high will allow more time for demagnetization, and often helps.

High pwm frequency is around 20kHz, and low pwm frequency is around 8kHz.

One benefit of using a low pwm frequency is that the step from almost full power to full power becomes smaller. On the other hand, 8kHz is in the audible frequency range, and also there is a step in power when the motor rotation frequency is equal to the pwm frequency.

Pwm damped light mode adds loss to the motor for faster retardation. Damped light mode always uses high pwm frequency.

In damped light mode, two motor terminals are shorted when pwm is off.

The damped light mode is only supported on some ESCs (where fet switching is sufficiently fast).

The rotation direction setting can be used to reverse motor rotation.

The input pwm polarity setting can be used to inverse the throttle behaviour. This is intended to be used with receivers that provide negative pwm (at least some Walkeras do). When using PPM input it must be set to positive.

Demag compensation is a feature to protect from motor stalls caused by long winding demagnetization time after commutation. The typical symptom is motor stop or stutter upon quick throttle increase, particularly when running at a low rpm. As described earlier, setting high commutation timing normally helps, but at the cost of efficiency.

The demag compensation is an alternative way of combating the issue. First of all, it detects when a demag situation occurs.

- In this situation, there is no info on motor timing, and commutation proceeds blindly with a predicted timing.

- In addition to this, motor power is cut off some time before the next commutation.

A metric is calculated that indicates how severe the demag situation is. The more severe the situation, the longer power is cut off.

When demag compensation is set to off, power is never cut.

When setting it to low or high, power is cut. For a high setting, power is cut more aggressively.

Generally, a higher value of the compensation parameter gives better protection.

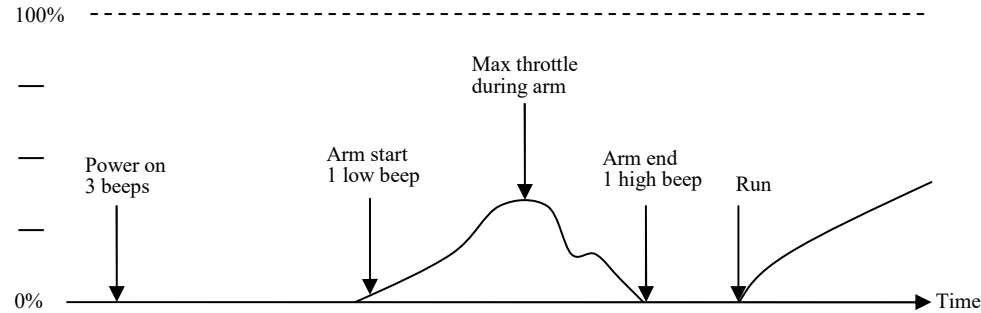
If demag compensation is set too high, maximum power can be somewhat reduced.

Programming parameters that can only be accessed from configuration software (BLHeliSuite):

- Throttle minimum and maximum values for PPM input (will also be changed by doing a throttle calibration).
- Throttle center value for bidirectional operation with PPM.
- Main motor spoolup time. Legal range is 1 to 17, values outside are clipped.
- Governor setup mode rpm target.
- Beep strength, beacon strength and beacon delay.
- Programming by TX. If disabled, the TX can not be used to change parameter values (default is enabled).
- Re-arming every start. If enabled, a new arming sequence will be required for every startup, not just the first after poweron (default is disabled).
- High/low BEC voltage for ESCs that support it (default is low).
- Thermal protection can be enabled or disabled (default is enabled).
- PWM input can be enabled or disabled (default is disabled). If disabled, only 1-2ms PPM and 125-250us OneShot125 are accepted as valid input signals. Set to disabled if using OneShot125 with looptimes below 1100.
- Power limiting for low RPMs can be enabled or disabled (default is enabled). Disabling it can be necessary in order to achieve full power on some low kV motors running on a low supply voltage. However, disabling it increases the risk of toasting motor or ESC.
- Brake on stop can be enabled or disabled (from rev14.5). When enabled, brake will be applied when throttle is zero. For nonzero throttle, this setting has no effect.

Arming sequence:

The figure below shows an example of throttle value versus time.



At power on, the ESC beeps 3 beeps.

For PWM input, the following applies:

When throttle is raised above zero, it beeps one low tone beep. This signals the start of the arming sequence.

When throttle is reduced to zero again, it beeps one high tone beep. This signals the end of the arming sequence.

For PPM input, the following applies:

When throttle signal is detected, it beeps one low tone beep. This signals the start of the arming sequence.

Then, when or if throttle is zero, it beeps one high tone beep. This signals the end of the arming sequence.

For a main motor esc running with PWM input, throttle is monitored during the arming sequence. The maximum value of throttle is recorded.

If governor arm mode is selected, this value will be used as the governor speed target when the motor starts running.

When running, the throttle input has no effect, as long as it is not below 20%.

Also, if 100% throttle is detected during the arming sequence, the ESC starts entering programming mode.

The main motor has a soft spoolup of some 3-10 seconds for full power. The spoolup is done in three phases, in order to be soft enough for the heli not to move, particularly before tail rpm is high enough to give some tail authority. In the first phase power is limited to the startup power for about one second. Then the power limit is slowly increased over the next three seconds. And in the final phase the power limit is increased more rapidly, until full power is available.

If the esc is armed and sees zero throttle for a given time, it beeps beacon beeps, which are about 1 beep per second

Auto bailout (for main):

The auto bailout works as described below.

The first start after powerup will always have a soft spoolup.

When the motor is fully spooled up, auto bailout is armed.

When auto bailout is armed, spoolup will be faster, with about 2 seconds for full power.

If then throttle is at a low non-zero value bailout remains armed. Even if the motor stops at times.

If a zero throttle value is seen, auto bailout is disarmed immediately, and the next spoolup will be soft.

Auto bailout only works for governed main motor operation.

For non-governed main motor operation, throttle response is always fast after spoolup is done.

Input signal:

The ESC accepts both positive and negative PWM, as well as PPM as input signal.

The type of input signal is auto detected during the arming sequence.

The only input signal that requires changing the default parameters, is negative PWM.

PWM is accepted as 12kHz, 8kHz (mCPX v1), 4kHz, 2kHz (several Walkeras) and 1kHz (mCPX v2).

PPM has a default throttle range of 1150us-1830us, and accepts rates from the normal 50Hz up to several hundred Hz.

Available throttle calibration range for PPM is from 1000us to 2000us, and the difference between minimum and maximum throttle must be more than 520us. If a calibration is done where the difference is less than 520us, the maximum will be shifted so that the difference is 520us.

OneShot125 mode works just the same as PPM mode, the only difference is that all timing is divided by 8.

Thermal protection:

The ESC measures temperature within the MCU and limits motor power if the temperature is too high.

Motor power is limited in four steps:

- If the temperature is above 140⁰C, motor power is limited to 75%.
- If the temperature is above 145⁰C, motor power is limited to 50%.
- If the temperature is above 150⁰C, motor power is limited to 25%.
- If the temperature is above 155⁰C, motor power is limited to 0%.

Stall protection:

From rev 14.2, the code also provides stall protection.

If the motor has attempted to start but not succeeded for a few seconds, it will stop attempting and wait for throttle to be zeroed before attempting again.

Braking / active freewheeling:

Damped light mode is implemented by doing braking, and inherently active freewheeling is also implemented. Then losses due to braking are counteracted by the reduced losses of active freewheeling.

Maximum speeds:

From rev 14.2, the code also provides overspeed protection.

Maximum speed is limited to 250k eRPM, at which point power to the motor is limited.

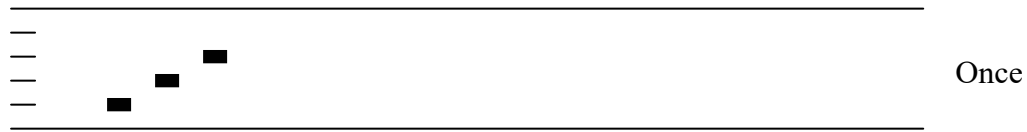
For ESCs with an MCU running at 48MHz, this number is 400k eRPM.

The maximum speed can be lower if running closed loop.

Beeps - Normal operation:

This procedure is used for PWM input signal.

Power up:



Throttle up detected (arming sequence start):



The maximum throttle in this interval sets the "arm" target for the governor.

Zero throttle detected (arming sequence end):

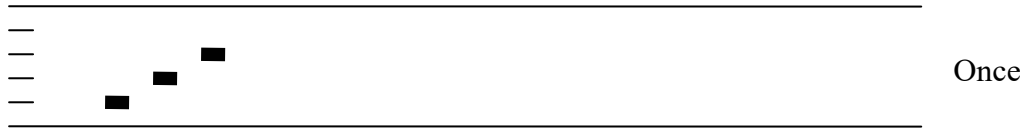


After this, the motor will run.

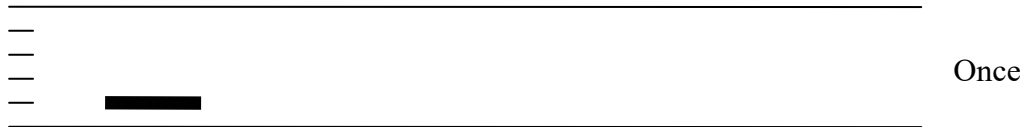
Beeps - Normal operation:

This procedure is used for PPM input signal.

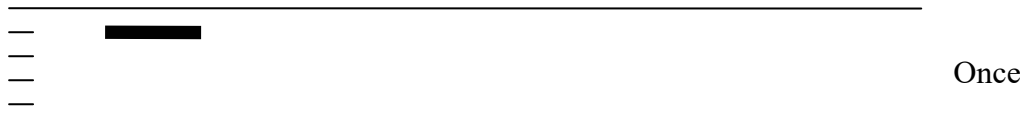
Power up:



Throttle signal detected (arming sequence start):



Zero throttle detected (arming sequence end):

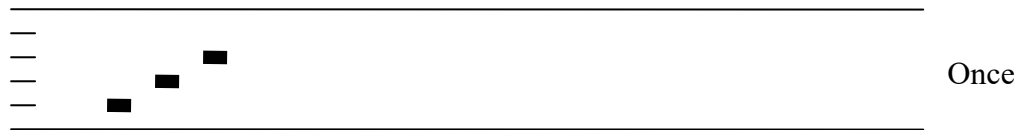


After this, the motor will run.

Beeps - Entering programming mode:

This procedure is used for PWM input signal.

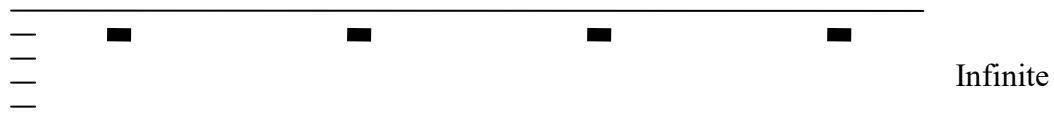
Power up:



Throttle up detected (arming sequence start):



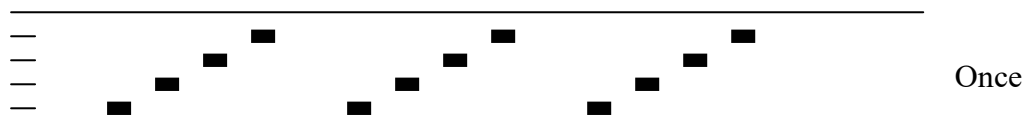
Full throttle detected (start of entering programming mode):



Zero throttle detected (continue entering programming mode):



Full throttle detected (programming mode entered):



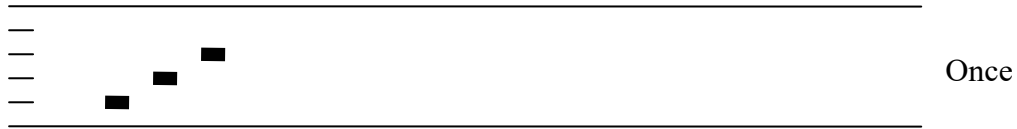
The above description is for main or multi.

For the tail, follow the same sequence, but use right rudder as full throttle and left rudder as zero throttle.

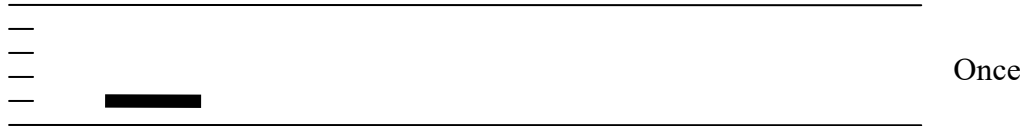
Beeps - Throttle calibration and entering programming mode:

This procedure is used for PPM input signal.

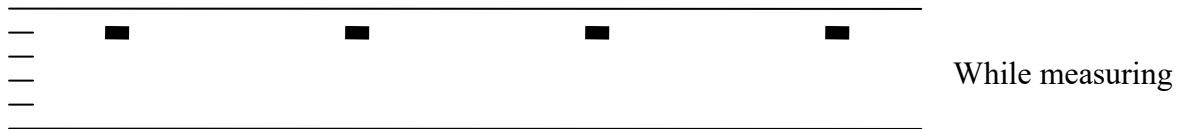
Power up:



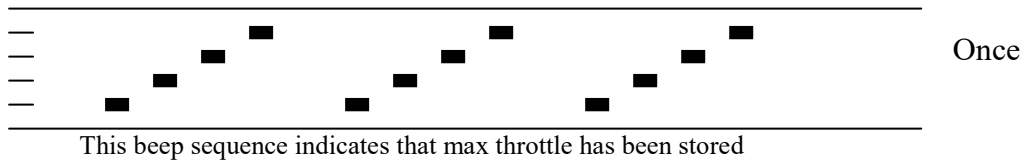
Throttle signal detected (arming sequence start):



When throttle is above midstick (measuring max throttle):



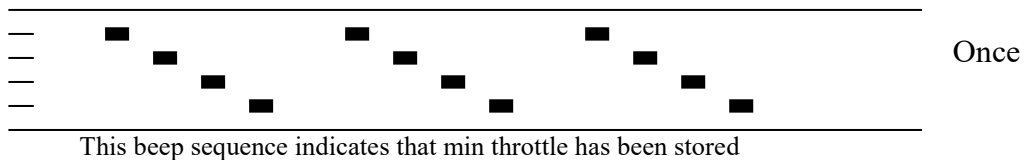
If throttle is above midstick for 3 seconds:



When throttle is below midstick (measuring min throttle):

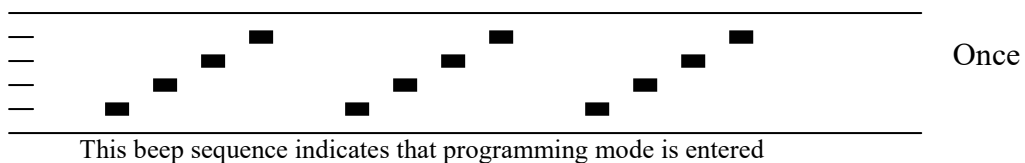


If throttle is below midstick for 3 seconds:



At this point throttle calibration values are stored. You may remove power from the ESC, if you just wanted to do a throttle calibration and not enter programming mode.

Full throttle detected:

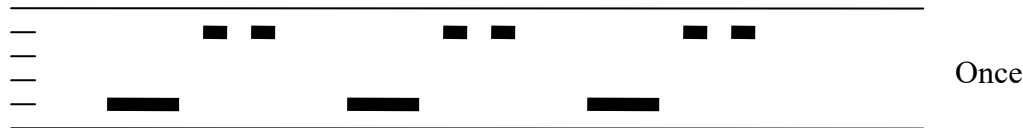


Beeps - Programming mode:

Function 1, parameter value 1



Function 1, parameter value 2



...etc...

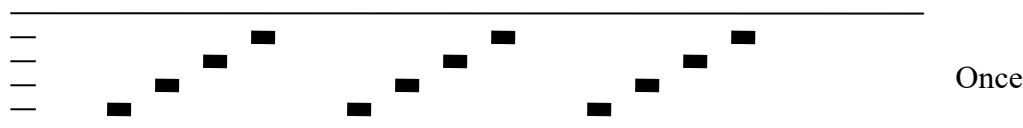
Function 2, parameter value 1



...etc...

If the throttle stick is moved to zero during one of the above sequences, the parameter value of that function is selected and stored. And you will hear this sound:

Parameter value stored



The ESC then resets itself.

If the throttle stick is moved below max (but not to zero), the current parameter will be skipped, and programming will proceed to the next parameter. This way it is possible to access the later parameters without going through all the beeps.

It is generally a good idea to go to full throttle again before selecting a parameter, to make sure you have selected the right parameter.

Throttle is read in the 1 second pause between the function/parameter beeps.

If the throttle stick is never moved to zero, the ESC will load the defaults and then reset itself after the last parameter value of the last function. This is a convenient way of setting all parameters to defaults.

If power is disconnected during the programming sequence, then no changes are done to the programmed values.

Revision history:

- Rev1.0: Initial revision based upon BLHeli for AVR controllers
- Rev2.0: Changed "Eeprom" initialization, layout and defaults
 - Various changes and improvements to comparator reading. Now using timer1 for time from pwm on/off
 - Beeps are made louder
 - Added programmable low voltage limit
 - Added programmable damped tail mode (only for 1S ESCs)
 - Added programmable motor rotation direction
- Rev2.1: (minor changes by 4712)
 - Added Disable TX Programming by PC Setup Application
 - therefore changed EEPROM_LAYOUT_REVISION = 8
 - Added Vdd Monitor as reset source when writing to "EEProm"
 - Changed for use of batch file to assemble, link and make hex files
- Rev2.2: (minor changes by 4712)
 - Added Disable Throttle Re-Arming every motor start by PC Setup Application
- Rev2.3: (minor changes by 4712)
 - Added bugfixed (2x CLR C before j(n)c operations)thx Steffen!
- Rev2.4: Revisions 2.1 to 2.3 integrated
- Rev3.0: Added PPM (1050us-1866us) as accepted input signal
 - Added startup rpm as a programming parameter
 - Added startup acceleration as a programming parameter
 - Added option for using voltage measurements to compensate motor power
 - Added governor target by setup as a governor mode option
 - Governor is kept active regardless of rpm
 - Smooth governor spoolup/down in arm and setup modes
 - Increased governor P and I gain programming ranges
 - Increased and changed low voltage limit programming range
 - Disabled tx programming entry for all but the first arming sequence after power on
 - Made it possible to skip parameters in tx programming by setting throttle midstick
 - Made it default not to rearm for every restart
- Rev3.1: Fixed bug that prevented chosen parameter to be set in tx programming
- Rev3.2: ...also updated the EEPROM revision parameter
- Rev3.3: Fixed negative number bug in voltage compensation

- Fixed bug in startup power calculation for non-default power
- Prevented possibility for voltage compensation fighting low voltage limiting
- Applied overall spoolup control to ensure soft spoolup in any mode
- Added a delay of 3 seconds from initiation of main motor stop until new startup is allowed
- Reduced beep power to reduce power consumption for very strong motors/ESCs
- Rev3.4: Fixed bug that prevented full power in governor arm and setup modes
 - Increased NFETON_DELAY for XP_7A and XP_12A to allow for more powerful fets
 - Increased initial spoolup power, and linked to startup power
- Rev4.0: Fixed bug that made tail tx program beeps very weak
 - Added thermal protection feature
 - Governor P and I gain ranges are extended up to 8.0x gain
 - Startup sequence is aborted upon zero throttle
 - Avoided voltage compensation function induced latency for tail when voltage compensation is not enabled
 - Improved input signal frequency detection robustness
- Rev4.1: Increased thermal protection temperature limits
- Rev5.0: Added multi(copter) operating mode. TAIL define changed to MODE with three modes: MAIN, TAIL and MULTI
 - Added programmable commutation timing
 - Added a damped light mode that has less damping, but that can be used with all escs
 - Added programmable damping force
 - Added thermal protection for startup too
 - Added wait beeps when waiting more than 10 sec for throttle above zero (after having been armed)
 - Modified tail idling to provide option for very low speeds
 - Changed PPM range to 1150-1830us
 - Arming sequence is dropped for PPM input, unless it is governor arm mode
 - Loss of input signal will immediately stop the motor for PPM input
 - Bug corrected in Turnigy Plush 6A voltage measurement setup
 - FET switching delays are set for original fets. Stronger/doubled/tripled etc fets may require faster pfet off switching
 - Miscellaneous other changes
- Rev6.0: Reverted comparator reading routine to rev5.0 equivalent, in order to avoid tail motor stops
 - Added governor range programmability
 - Implemented startup retry sequence with varying startup power for multi mode
 - In damped light mode, damping is now applied to the active nfet phase for fully damped capable ESCs
- Rev6.1: Added input signal qualification criteria for PPM, to avoid triggering on noise spikes (fix for plush hardware)
 - Changed main and multi mode stop criteria. Will now be in run mode, even if RC pulse input is zero

- Fixed bug in commutation that caused rough running in damped light mode
- Miscellaneous other changes
- Rev7.0 Added direct startup mode programmability
 - Added throttle calibration. Min \geq 1000us and Max \leq 2000us. Difference must be >520 us, otherwise max is shifted so that difference=520us
 - Added programmable throttle change rate
 - Added programmable beep strength, beacon strength and beacon delay
 - Reduced power step to full power significantly
 - Miscellaneous other changes
- Rev8.0 Added a 2 second delay after power up, to wait for receiver initialization
 - Added a programming option for disabling low voltage limit, and made it default for MULTI
 - Added programable demag compensation, using the concept of SimonK
 - Improved robustness against noisy input signal
 - Refined direct startup
 - Removed voltage compensation
 - Miscellaneous other changes
- Rev9.0 Increased programming range for startup power, and made it's default ESC dependent
 - Made default startup method ESC dependent
 - Even more smooth and gentle spoolup for MAIN, to suit larger helis
 - Improved transition from stepped startup to run
 - Refined direct startup
- Rev9.1 Fixed bug that changed FW revision after throttle calibration or TX programming
- Rev9.2 Altered timing of throttle calibration in order to work with MultiWii calibration firmware
 - Reduced main spoolup time to around 5 seconds
 - Changed default beacon delay to 3 minutes
- Rev9.3 Fixed bug in Plush 60/80A temperature reading, that caused failure in operation above 4S
 - Corrected temperature limit for HiModel cool 22/33/41A, RCTimer 6A, Skywalker 20/40A, Turnigy AE45A, Plush 40/60/80A. Limit was previously set too high
- Rev9.4 Improved timing for increased maximum rpm limit

- Rev10.0 Added closed loop mode for multi
 - Added high/low BEC voltage option (for the ESCs where HW supports it)
 - Added method of resetting all programmed parameter values to defaults by TX programming
 - Added Turnigy K-force 40A and Turnigy K-force 120A HV ESCs
 - Enabled fully damped mode for several ESCs
 - Extended startup power range downwards to enable very smooth start for large heli main motors
 - Extended damping force with a highest setting
 - Corrected temperature limits for F310 chips (Plush 40A and AE 45A)
 - Implemented temperature reading average in order to avoid problems with ADC noise on Skywalkers
 - Increased switching delays for XP 7A fast, in order to avoid cross conduction of N and P fets
 - Miscellaneous other changes
- Rev10.1 Relaxed RC signal jitter requirement during frequency measurement
 - Corrected bug that prevented using governor low
 - Enabled vdd monitor always, in order to reduce likelihood of accidental overwriting of adjustments
 - Fixed bug that caused stop for PPM input above 2048us, and moved upper accepted limit to 2160us
- Rev10.2 Corrected temperature limit for AE20-30/XP7-25, where limit was too high
 - Corrected temperature limit for 120HV, where limit was too low
 - Fixed bug that caused AE20/25/30A not to run in reverse
- Rev10.3 Removed vdd monitor for 1S capable ESCs, in order to avoid brownouts/resets
 - Made auto bailout spoolup for main more smooth
- Rev10.4 Ensured that main spoolup and governor activation will always be smooth, regardless of throttle input
 - Added capability to operate on 12kHz input signal too

- Rev11.0 Fixed bug of programming default values for governor in MULTI mode
 - Disabled interrupts explicitly some places, to avoid possibilities for unintentional fet switching
 - Changed interrupt disable strategy, to always allow pwm interrupts, to avoid noise when running at low rpms
 - Added governor middle range for MAIN mode
 - Added bidirectional mode for TAIL and MULTI mode with PPM input
 - Changed and improved demag compensation
 - Miscellaneous other changes
- Rev11.1 Fixed bug of slow acceleration response for MAIN mode running without governor
 - Fixed bug with PWM input, where throttle remains high even when zeroing throttle (seen on V922 tail)
 - Fixed bug in bidirectional operation, where direction change could cause reset
 - Improved autorotation bailout for MAIN
 - Reduced min speed back to 1220 erpm
 - Misc code cleanups
- Rev11.2 Fixed throttle calibration bug
 - Added high side driver precharge for all-nfet ESCs
 - Optimized timing in general and for demag compensation in particular
 - Governor is deactivated for throttle inputs below 10%
 - Auto bailout functionality modified
 - Increased beacon delay times
- Rev12.0 Added programmable main spoolup time
 - Added programmable temperature protection enable
 - Bidirectional mode stop/start improved. Motor is now stopped before starting
 - Power is limited for very low rpms (when BEMF is low), in order to avoid sync loss
 - Damped light mode is made more smooth and quiet, particularly at low and high rpms
 - Comparator signal qualification scheme is changed
 - Demag compensation scheme is significantly changed
 - Increased jitter tolerance for PPM frequency measurement
 - Fully damped mode removed, and damped light only supported on damped capable ESCs
 - Default tail mode changed to damped light
 - Miscellaneous other changes
- Rev12.1 Fixed bug in tail code
 - Improved startup for Atmel
 - Added support for multiple high BEC voltages
 - Added support for RPM output

- Rev12.2 Improved running smoothness, particularly for damped light
 - Avoiding lockup at full throttle when input signal is noisy
 - Avoiding detection of 1-wire programming signal as valid throttle signal
- Rev13.0 Removed stepped start
 - Removed throttle change rate and damping force parameters
 - Added support for OneShot125
 - Improved commutation timing accuracy
- Rev13.1 Removed startup ramp for MULTI
 - Improved startup for some odd ESCs
- Rev13.2 Still tweaking startup to make it more reliable and faster for all ESC/motor combos
 - Increased deadband for bidirectional operation
 - Relaxed signal detection criteria
 - Added support for running 48MHz capable SiLabs MCUs at 48MHz
 - Added bootlader to SiLabs code
 - Miscellaneous other changes
- Rev14.0 Improved running at high timing
 - Improved running at high RPMs and increased max RPM limit
 - Avoid being locked in bootloader (implemented in Suite 13202)
 - Improved reliability of 3D (bidirectional) mode and startup
 - Smoother running and greatly reduced step to full power in damped light mode
 - Removed low voltage limiting for MULTI
 - Added pwm dither parameter
 - Added setting for enable/disable of low RPM power protection
 - Added setting for enable/disable of PWM input
 - Better AFW and damping for some ESCs (that have a slow high side driver)
 - Miscellaneous other changes
- Rev14.1 Fixed max throttle calibration bug (for non-oneshot)
 - Fixed some closed loop mode bugs
 - Relaxed signal jitter requirement for looptimes below 1000
 - Added skipping of damping fet switching near max power, for improved high end throttle linearity, using the concept of SimonK
 - Improved sync hold at high rpms
- Rev14.2 Added stalled motor shutoff after about 10 seconds (for tail and multi code with PPM input)
 - Greatly increased maximum rpm limit, and added rpm limiting at 250k erpm (48MHz MCUs at 400k erpm)
 - Improved bidirectional operation

- Rev14.3 Moved reset vector to be just before the settings segment, in order to better recover from partially failed flashing operation
 - Added 100ms initialization delay for the Graupner Ultra 20A ESC
 - Shortened stall detect time to about 5sec, and prevented going into tx programming after a stall
 - Optimizations of software timing and running reliability
- Rev14.4 Improved startup, particularly for larger motors
 - Improved running at very high rpms
 - Made damped light default for MULTI on ESCs that support it
 - Miscellaneous other changes
- Rev14.5 Longer between beacon beeps (to reduce motor heating), and now again beeping on two motor phases
 - Implemented programmable brake on zero throttle
 - Implemented hardware reload of commutation timers, to reduce sensitivity to interrupt activity on high rpms
 - Implemented support for EN/PWM style fet drivers
 - Slightly modified throttle calibration
 - Improved startup, particularly for small motors
 - Improved smoothness
- Rev14.6 Fixed bug that caused tail motor not to stop
 - Fixed bug that caused brake not to work for low side pwm ESCs
 - Fixed bug where noisy input signal could cause loss of sync
 - Increased fet deadtime a bit for the LB20A and the LB20A pro
 - Made low rpm power limiting programmable through the startup power parameter