

```
nmea.client=""
imu.rate=20
imu.alignmentQ=[0.6989714933401847, -0.7151191791740817,
0.006588708157132007, 0.0]
imu.heading_offset=0.0000
wind.offset=0.0000
wind.sensors_height=0.0000
rudder.offset=0.0
rudder.scale=-1.375
rudder.nonlinearity=0.0
rudder.range=30.0000
apb.xte.gain=300.0000
servo.faults=0
servo.max_current=4.5000
servo.current.factor=1.0000
servo.current.offset=0.0000
servo.voltage.factor=1.0000
servo.voltage.offset=0.0000
servo.max_controller_temp=60.0000
servo.max_motor_temp=60.0000
servo.max_slew_speed=27.9528
servo.max_slew_slow=33.8583
servo.gain=1.0000
servo.clutch_pwm=100.0000
servo.use_brake=false
servo.period=0.4000
servo.compensate_current=false
servo.compensate_voltage=false
servo.amp_hours=0.8181903547141781
servo.hardover_time=10.0000
servo.speed.min=50.0000
servo.speed.max=100.0000
servo.position.p=0.1500
servo.position.i=0.0000
servo.position.d=0.0200
servo.use_eeprom=true
servo.disengage_on_timeout=true
ap.mode="compass"
ap.pilot.absolute.P=0.0500
ap.pilot.absolute.I=0.0000
ap.pilot.absolute.D=0.2000
ap.pilot.absolute.DD=0.0000
ap.pilot.simple.P=0.0050
ap.pilot.simple.I=0.0000
ap.pilot.simple.D=0.1500
ap.pilot.basic.P=0.0030
ap.pilot.basic.I=0.0000
ap.pilot.basic.D=0.0900
ap.pilot.basic.DD=0.0750
ap.pilot.basic.PR=0.0050
ap.pilot.basic.FF=0.6000
ap.pilot.basic2.P=0.0030
ap.pilot.basic2.I=0.0000
ap.pilot.basic2.D=0.0900
ap.pilot.basic2.DD=0.0750
ap.pilot.basic2.PR=0.0050
ap.pilot.basic2.FF=0.6000
ap.pilot.basic3.P=0.0030
```

```
ap.pilot.basic3.I=0.0000
ap.pilot.basic3.D=0.0900
ap.pilot.basic3.DD=0.0750
ap.pilot.basic3.PR=0.0050
ap.pilot.basic3.FF=0.6000
ap.pilot="basic"
ap.tack.delay=0.0000
ap.tack.angle=100.0000
ap.tack.rate=15.0000
ap.tack.threshold=50.0000
ap.tack.count=0
imu.gyrobias=[0.076, 0.014, -0.019]
imu.accel.calibration.locked=true
imu.accel.calibration.points=[[1.015, -0.032, -0.073], [0.053, -0.061,
1.000], [-0.982, -0.055, -0.001], [1.018, -0.034, 0.008], [-0.014, -
1.014, 0.222], [0.035, -1.039, 0.013], [0.021, -0.002, -1.008], [-0.067,
0.059, -1.000], [0.003, 0.964, 0.009], [-0.009, 0.959, 0.099], [1.016, -
0.033, 0.057], [0.053, -0.063, 1.000]]
imu.compass.calibration.locked=true
imu.compass.calibration.points=[[5.940, -13.058, 7.286], [5.785, -13.462,
8.335], [6.338, -12.524, 8.508], [5.279, -13.025, 6.322], [5.077, -
13.206, 5.096], [4.390, -13.768, 5.890], [6.551, -12.903, 12.680],
[7.320, -12.750, 14.630], [6.003, -13.522, 22.448], [-3.256, -10.855,
35.106], [-4.960, -13.570, 40.070], [-55.585, -13.723, 13.048], [3.790, -
13.850, 3.590], [-40.216, -14.533, -14.585], [1.225, -11.537, 31.387],
[5.220, -13.180, 2.770], [-52.630, -13.630, 27.830], [-51.542, -13.685, -
3.055], [-29.249, -11.721, 44.313], [-54.708, -12.451, 20.840], [-38.705,
-12.445, 40.920], [-54.665, -13.562, 7.096], [-44.388, -13.580, 36.558],
[-47.619, -14.123, -9.019], [-17.225, -12.125, 42.922]]
signalk.period=0.5000
signalk.uid="pypilot"
nmea.gps_id="APRMC"
gps.filtered.enabled=false
```