Sample PID settings of actual builds.

H8 Stock settings:
pid.c:
float pidkp[PIDNUMBER] = { 17.0e-2, 17.0e-2, 10e-1 };
float pidki[PIDNUMBER] = { 15e-1, 15e-1, 50e-1 };
float pidkd[PIDNUMBER] = { 6.8e-1, 6.8e-1, 5.0e-1 };

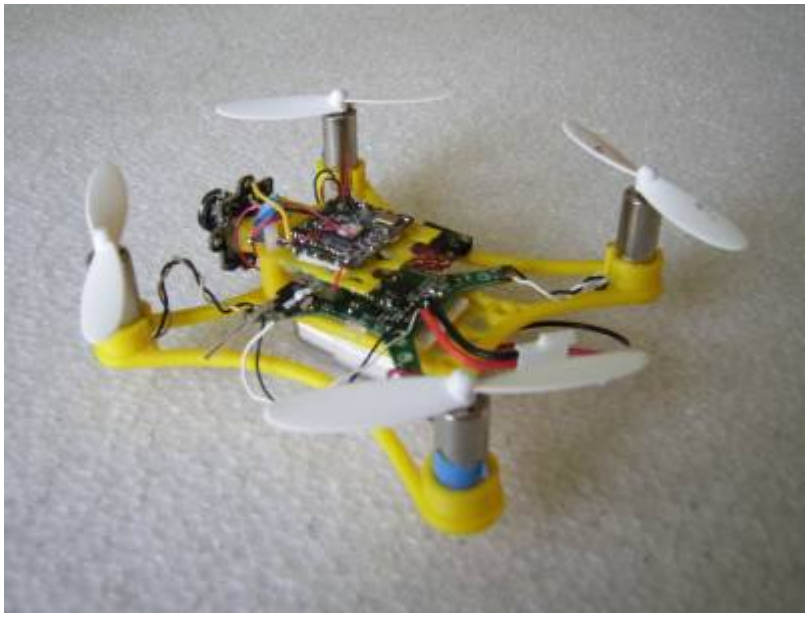
angle_pid.c:
float apidkp[APIDNUMBER] = { 2.2e-2, 2.2e-2, 0e-1 };
float apidki[APIDNUMBER] = { 1.0e-2, 1.0e-2, 0e-1 };

JJRC J-1000

- size (between motor shafts): 65mm x 65mm / diagonal 95mm
- 7x20mm motors, direct drive, Hubsan x4 propellers

pid.c
float pidkp[PIDNUMBER] = { 14.0e-2, 14.0e-2, 25e-1 };
float pidki[PIDNUMBER] = { 10e-1, 10e-1, 13e-1 };
float pidkd[PIDNUMBER] = { 6.0e-1, 6.0e-1, 2.0e-1 };

angle_pid.c
float apidkp[APIDNUMBER] = { 1.6e-2, 1.6e-2, 0e-1 };
float apidki[APIDNUMBER] = { 0.6e-2, 0.6e-2, 0e-1 };



8.5mm custom build by Silverxxx
- size: 8cm sides, 11 diagonal
- 8.5x20mm motors, direct drive, DM007 props
- frame:http://www.thingiverse.com/thing:1221911
- auw 47g inc. 360mAh 1S and fpv

pid.c
```
float pidkp[PIDNUMBER] = { 17.0e-2, 17.0e-2, 5e-1 };
float pidki[PIDNUMBER] = { 8e-1, 8e-1, 5e-1 };
float pidkd[PIDNUMBER] = { 6.8e-1, 6.8e-1, 5.0e-1 };
```

angle_pid.c
```
float apidkp[APIDNUMBER] = { 1.8e-2, 1.8e-2, 0e-1 };
float apidki[APIDNUMBER] = { 1.0e-2, 1.0e-2, 0e-1 };
```

config.h
```
#define MOTOR_CURVE_85MM_8KHZ
#define PWM_8KHZ
// software gyro lpf
#define SOFT_LPF_4TH_088HZ
// this is not really necessary, but i think i like it
#define CLIP_FF
```

8.5mm Geared Frankenquad Based on WLToys V212
- Frame: WLToys V212 (upgraded V949) 230mm diagonal between the blade shafts (centre of a blade)
- 8.5x20mm motors, geared (1:6 ratio)
- Propellers: Original V212 5,5“ size
- AUW: 73gr

pid.c
```
float pidkp[PIDNUMBER] = { 10e-2, 10e-2, 7e-1 };
float pidki[PIDNUMBER] = { 3e-1, 3e-1, 7e-1 };
float pidkd[PIDNUMBER] = { 6e-1, 6e-1, 5e-1 }
```

angle_pid.c
float apidkp[APIDNUMBER] = { 1.5e-2, 1.5e-2, 1.2e-3 };
float apidki[APIDNUMBER] = { 4e-2, 4e-2, 1e-2 };

config.h
#define SOFT_LPF_4TH_088HZ
#define MOTOR_CURVE_85MM_32KHZ
#define PWM_32KHZ