

## Pejlingsretteskema

St.K.Dv.= \_\_\_\_\_

Over styrekompas med deviation.

**Fra kompas**

P. Dv. \_\_\_\_\_

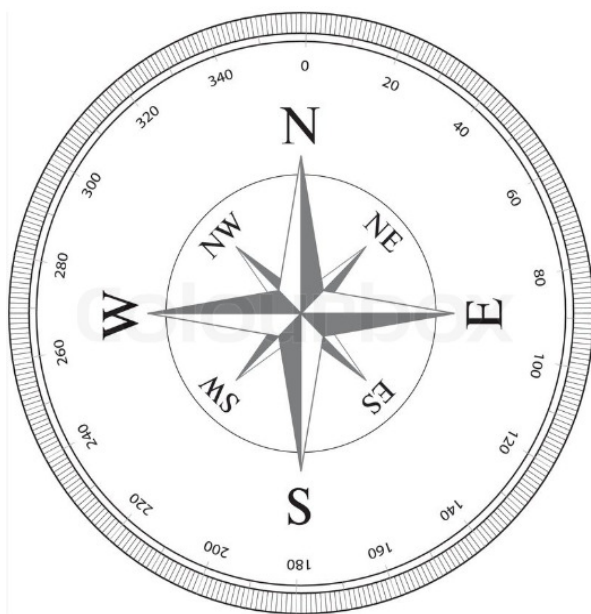
(V = minus, Ø = plus) dv. \_\_\_\_\_

P. Mv. \_\_\_\_\_

(V = minus, Ø = plus) mv. \_\_\_\_\_

**Til søkort**

P. Rv. \_\_\_\_\_



St.K.Dv.= \_\_\_\_\_

Over styrekompas med deviation.

**Fra kompas**

P. Dv. \_\_\_\_\_

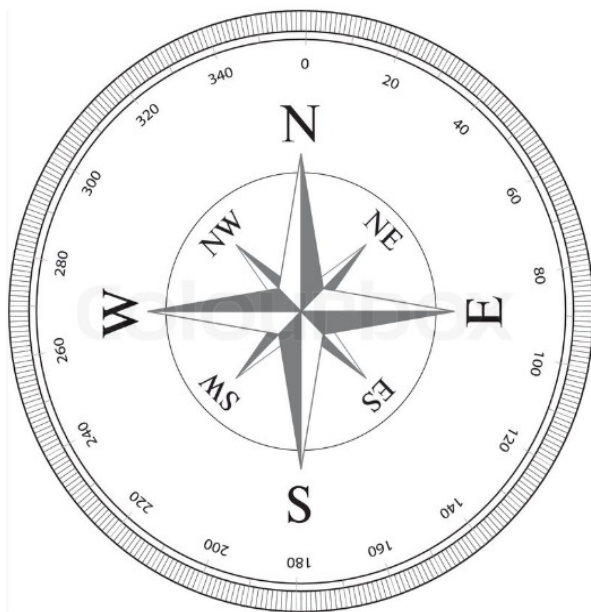
(V = minus, Ø = plus) dv. \_\_\_\_\_

P. Mv. \_\_\_\_\_

(V = minus, Ø = plus) mv. \_\_\_\_\_

**Til søkort**

P. Rv. \_\_\_\_\_



St.K.Dv.= \_\_\_\_\_

Over styrekompas med deviation.

**Fra kompas**

P. Dv. \_\_\_\_\_

(V = minus, Ø = plus) dv. \_\_\_\_\_

P. Mv. \_\_\_\_\_

(V = minus, Ø = plus) mv. \_\_\_\_\_

**Til søkort**

P. Rv. \_\_\_\_\_

