

WinFrog Device Group:	GYRO
Device Name/Model:	ROBERTSON AP9 (Autopilot)
Device Manufacturer:	Kongsberg Simrad Mesotech Ltd (Maritime Dept.) 202 Brownlow Avenue Dartmouth N.S. B3B 1T5 Tel: +1 902 468 2268 Fax: +1 902 468 2217 E-Mail: sales@kongsberg-simrad.ns.ca www.simrad.no
Device Data String(s) Output to WinFrog:	"Heading: %05.1f" (last 4 digits of output string)
WinFrog Data String(s) Output to Device:	Nil
WinFrog .raw Data Record Type(s):	Type 910 (Type 410 if data repeated 15 times)

DEVICE DESCRIPTION:

The Robertson AP9 MK3 Autopilot has the ability to interface to almost any magnetic or gyrocompass, steering gear and navigation receiver. The unit is capable of dual compass input, as well as thruster control. All mode selection and steering parameter settings are made using touch buttons. It can accept information from navigation receivers and plotters to combine steering and validation. The AP9 can be configured to output received heading data in a proprietary format to WinFrog.



Robertson AP9 MK3

DEVICE CONFIGURATION INSTRUCTIONS (Suggested):

Baud Rate: 9600

Data Bits: 8

Stop Bits: 1

Parity: None

The manufacturer claims that the AP9 can be interfaced to 'virtually any type of steering gear'. Therefore the unit is most likely of numerous configurable communication

parameters. Refer to the operator's manual for configuring the AP9's serial communication parameters.

WINFROG I/O DEVICES > CONFIG OPTIONS:

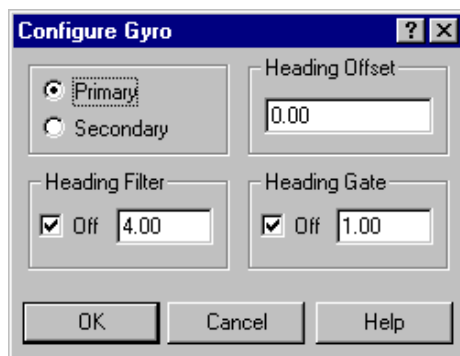
The Robertson AP9 is added to WinFrog from the Gyro device category. Adding the Robertson AP9 to Winfrog creates a Heading Data Item in WinFrog.

When adding the Robertson AP9 to WinFrog, the communication parameters must be set to match the communication settings in the AP9.

No device configuration is required or available at the "generic" I/O Device window level.

WINFROG VEHICLE - DEVICE > EDIT OPTIONS:

Once the Robertson AP9 device has been added to a vehicle's device list, it must be edited to suit the application. In the vehicle's device list, highlight the Robertson device and click the Edit button. The Configure Gyro dialog box appears as seen below.



Calculation (Primary/Secondary):

Set the type of calculation to Primary or Secondary by selecting the appropriate radio button. Devices set to Primary are used to provide the vehicle heading information. Devices set to Secondary are simply monitored, and are not used in the vehicle's calculations.

In the case of Primary device failure, WinFrog will not automatically use the Secondary device(s). You must manually change a Secondary device to Primary status in order for it to be used in the vehicle's calculations.

Heading Offset:

A correction value (as determined from a gyro calibration) can be input in the Heading Offset box. This value is added to the heading value from the Robertson AP9 to provide a corrected heading for the vehicle. Note that positive or negative values can be entered.

Heading Filter/Heading Gate:

The Heading Filter is used to "smooth" heading values used by the vehicle. The value entered in the Heading Filter indicates the number of headings that will be

used to predict the next heading value. The larger the value entered, the “heavier” the filter will be – i.e. the slower the vehicle’s heading will respond to changes.

The Heading Gate defines a tolerance value to limit the use of anomalies in gyro readings. If the next observed gyro value received falls outside the specified range of predicted values (i.e. plus or minus the entered value), the value will not be used.

CONFIGURATION DETAILS:

Refer to the Operators’ Manual for configuration details on the Robertson AP9.

The compatibility of this driver with other Robertson Products is unknown.