

Dynamic Positioning



Engine and Rudder control

Throttle and shift control for single and twin screw vessels. Suitable for mechanical and electronic engines and gear boxes. Up to eight helm stations possible.

Super soft Shifting

When a Trolling Valve is available, clutch pressure is increased steadily, not abruptly. Clutch engagement will be gentle.



Slow Mode

When maneuvering at low speed, the propulsion and steering system changes automatically or manually into Slow Mode. This will ready Thrusters and Engines and Trolling Valves, when needed.



Rudder, Throttle and Thruster control

Heading is gyro stabilized. Putting the electric helm in its center detent will draw a straight line on your plotter. By deflecting the wheel, a rate of turn is selected. Thruster-Joysticks at each station are for direct individual Thruster control.

Steering by Joystick

Simply move or twist the Hover-Joystick into the direction you want your boat to move.

Speed Mode

Select GND Speed or Water Speed when towing gear

Hover-Mode - Dynamic Positioning (DP)

By pressing a button, the vessel stops automatically and holds its present position. Accuracy is within 0.2 meters, conditions permitting. Modify Heading by twisting the Joystick or digitally select Heading or Wind Angle



Hover-Joystick

Profile Mode

Profile Mode can be activated in NAV or LAND Mode. The vessel will then slow down and come to a halt in GPS Anchor Mode at the upcoming way point.



SLIDE Mode

While the vessel is precisely following a route, the desired speed and Heading can be selected independently. For example 0.6 kn along the route and a Heading of 270, while the route track is 120.



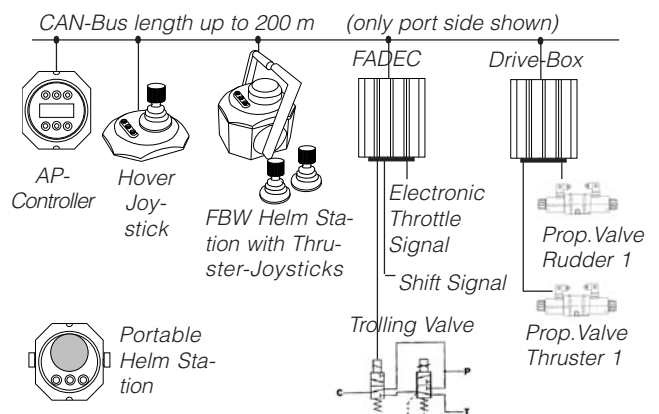
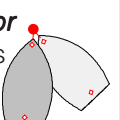
Setting the Pivot Point on the boat

When turning in Hover Mode, the Pivot Point remains at the same map position. Select a rear Pivot Point,



when the crew is working at the stern.

When desired use the economic **Anchor Mode**, also called Fish Point. The vessel is tied to a virtual buoy at the bow or stern. Thrusters are not used in this mode. Heading is established by wind and current.



Two CAN-Bus branches - port und stbd - make a redundant system.

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