Regatta Processor software development

- ➢ V1.9
  - ➢ Addition of channel true heading and true Wind Direction
- ➢ V2.0
  - ➢ Calculation of the wind direction over ground
  - ➢ Calculation of the wind speed over ground
  - ➢ Auto-detection of the 3D hull (V1, V2, compass Regatta, KVH)
  - ➢ Management of the offsets in mode heading CAP MAG2 (KVH or NMEA)
  - ➢ Addition of the function of the Regatta compass Autocompensation
  - ➢ Addition of filtering of heading, roll and pitch in the Regatta compass
- ➢ V2.1
  - ➢ fixed bugs
- ➢ V2.2
  - ➢ Management of the degraded mode boat speed. If boat speed US not locked, calculation on speed over ground and display "Pan".
  - ➢ Authentication of the elements of the Topline bus to the creation of the list. If the firmwares are not update, non-startup of the Processor
  - ➢ Change in the handling of the blue led V2.3
  - ➢ Limitation of calculating angle of heel up to 60 °
  - ➢ Limitation of calculating pitch angle up to 40 °
  - ➢ Adding an error message when data 3DH is outlier
- ➢ V2.4
  - ➢ Compatibility with the Topline GPS
- ➢ V2.5
  - ➢ Compatibility with the latest firmware of the V2 3DH
  - ➢ Correction sign on the pitch
  - ➢ Addition of multifunction graphic authentication
- ➢ V2.6
  - ➢ Correction of the loss of a NMEA source after a timeout (e.g. during a stall GPS)
- ➢ V2.7
  - ➢ Addition of identifiers of the wifi interfaces
  - ➢ Quick scan of the Multifunction graphic for the Gyropilot

- V3.2
  - Fixed a bug on the noise-free wind.
  - Coefficients noise-free wind, to settle in "Constant" following the compass sensor:

    Coef1 : attitude filter

    Coef2 : AVA filter

    Coef3 : Pitch coef.

    Coef4 : Roll coef.

    Default setting

    Coef1 = 10

    Coef2 = 7

    Coef3 = - 1

    Coef4 = 1

    3DH_V2 (optimized)

    Coef1 = 6

    Coef2 = 3

    Coef3 = - 1

    Coef4 = 1

    KVH (optimized)

    Coef1 = 4

    Coef2 = 3

    Coef3 = -0.76

    Coef4 = 0.76

- V3.7
  - Compatibility with 3D Fusion
  - Correction of the Crash Processor when the baudrate NMEA is badly configured
  - Not compatible with Sailtune V2.1

- ➢ V3.9
  - ➢ Compatibility with 3D sensor V3
  - ➢ Compas calibration integrate on the processor web page (for 3D Sensor V3)
  - ➢ Compatibility with Paddle Wheel