SIMRAD®

ADDENDUM, software release 20.0 for:
- ## NSO evo2
- ## NSO evo3

This addendum documents the new features included in this software release.

Feature	Page
Device registration	3
Simrad mobile app available	3
The synchronize feature	3
WM-4 satellite receiver support [1]	4
FLIR M-232 IP camera support [1]	4
LiveSight support [1]	4
Power-Pole Charge module [2]	4
Ghost trolling motor support	5
Rhodan trolling motor support	5
The autopilot controller for trolling motor	6

[1] This feature is not available for NSO evo2.

[2] This feature is included in NSO evo2 software release 20.0. It was added to NSO evo3 in software release 19.1 and it is also included in software release 20.0.

Device registration

You are prompted to register your device during startup. You can also register it by following the instructions when selecting the registration option in the system settings dialog or system controls dialog.

Simrad mobile app available

The Simrad mobile app is now available for download from the Apple and Play stores.

Check the app at the app store to see what versions of the operating system are supported.

Use the Simrad mobile app to:

- Register your device
- Get customer support for your device
- Get up-to-date charts and offline maps
- Access manuals, guides and more
- Download software updates
- Cloud synchronize waypoints, routes and tracks

The synchronize feature

The C-MAP Embark button in the system controls dialog is replaced with a Synchronize my data button. The C-MAP Embark option in the Services Settings dialog is also replaced with a Synchronize my data option.

Example of the Synchronize my data button in the system controls dialog:
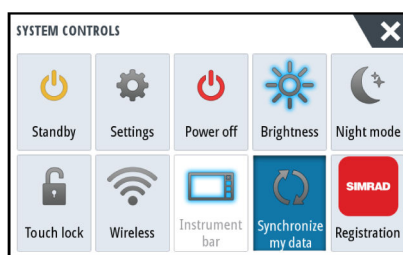
Using the synchronize feature

You can use a browser to sign-in at www.letsembark.io or you can sign-in to your Simrad app account from your mobile device or tablet to manage (create new, change, move, and delete):

- Waypoints
- Routes
- Tracks

Use the MFD's Synchronize my data option to synchronize between the MFD and your Simrad app account.

Requirements

- An account with the Simrad mobile app

➔ **Note:** Your C-MAP Embark or C-MAP app account credentials can be used to sign-in to the mobile app. You do not need to create a separate mobile app account.

- To synchronize, the unit must be connected to the internet. To connect the unit to the internet, refer to the operator manual.

Synchronizing

To synchronize the MFD data and your Simrad app account data (includes your data at www.letsembark.io), open the Synchronize my data feature from the System Controls dialog or the Services settings dialog.

After sign-in, the system advises the last time synchronizing occurred and the following options are available:
- Edit - use to change sign-in credentials
- Auto Synchronize - synchronizing occurs periodically in the background when connected to the internet
- Synchronize now - synchronizing occurs immediately
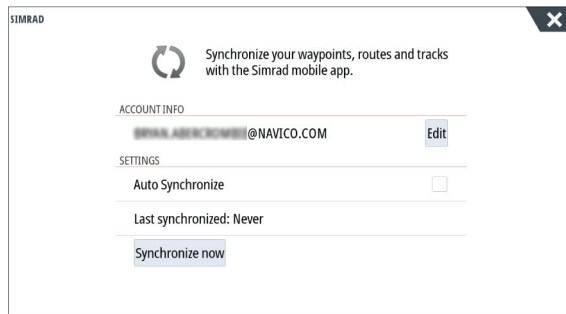

Navico WM-4 marine satellite receiver support

The Navico WM-4 marine satellite weather/audio receiver is supported. When the Navico WM-4 receiver is connected to your system and if you have the appropriate SiriusXM subscription you can include SiriusXM marine weather services and SiriusXM radio on your system.

➔ **Note:** SiriusXM weather is available for North America only.

➔ **Note:** This feature is not available for NSO evo2.

FLIR M-232 IP camera support

➔ **Note:** This feature is not available for NSO evo2.

If a FLIR M-232 IP camera is available on the Ethernet network, enable the feature in the Advanced settings dialog. Enabling the feature allows you to display the video and control the camera from the unit.
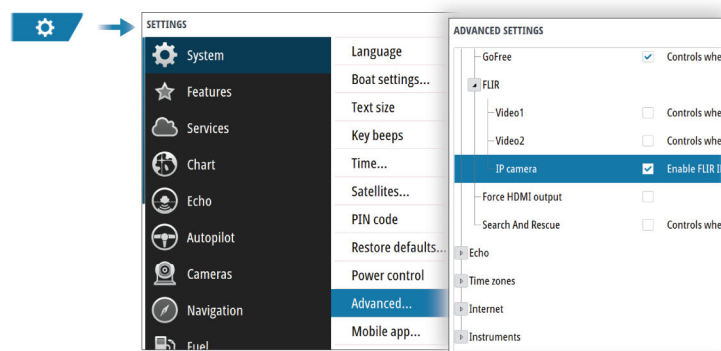

LiveSight support

➔ **Note:** This feature is not available for NSO evo2.

LiveSight Forward and LiveSight Down views are supported. When you connect a LiveSight transducer to your system and configure the setup of the transducer, the corresponding LiveSight app button will appear on the home page.

➔ **Note:** A sonar module connected to a PSI-1 module and a LiveSight transducer are required to enable LiveSight support.

Power-Pole Charge module

The Power-Pole battery charge management system displays battery status information.
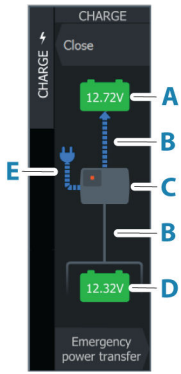
For installation, wiring and setup information, refer to the Power-Pole documentation supplied with the charge module.

|	
A	Engine battery/batteries
B	Battery connections
C	Power-Pole charge module
D	Auxiliary battery/batteries
E	Charge module AC power source connection

Battery icons

Color	Indicates
Green	Good level
Yellow	Marginal level
Red	Failing/critical level

Battery and AC source connections

Color	Indicates
Blue	Current flow
Grey	No current flow

Emergency power transfer

If your engine battery is low and you want to transfer power from the aux battery to the engine battery, select this option.
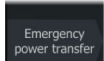
> ⚠ Warning: Using a battery at a very low charge level can damage the battery.

Ghost trolling motor support

The Ghost trolling motor is supported.

To control the Ghost trolling motor, refer to *"The autopilot controller for trolling motor"* on page 6.

To configure the Ghost foot pedal keys, refer to *"Configure the Ghost trolling motor foot pedal keys"* on page 10.

Rhodan trolling motor support

If a Rhodan trolling motor is connected to the NMEA 2000 network, the trolling motor is supported and can be controlled from the MFD. For more information about this trolling motor, refer to Rhodan.

To control the Rhodan trolling motor, refer to *"The autopilot controller for trolling motor"* on page 6.
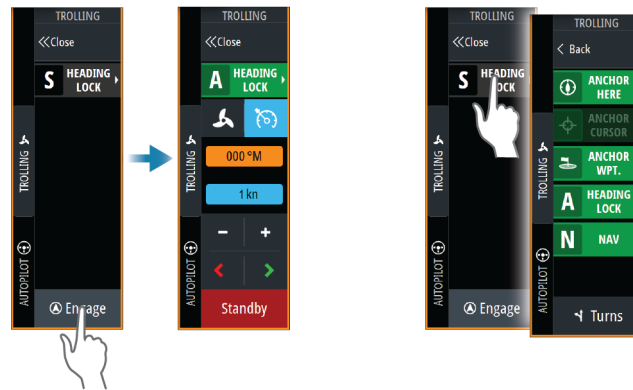
The autopilot controller for trolling motor
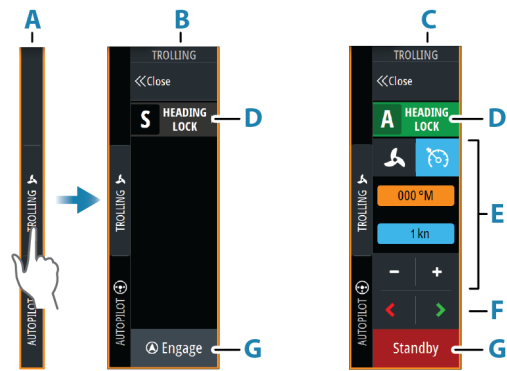
A	Control bar
B	Autopilot controller, disengaged
C	Autopilot controller, engaged
D	Mode button
E	Mode dependent information
F	Mode dependent buttons
G	Engage/Standby button

When the autopilot controller is the active panel, it is outlined with a border.

Engaging and disengaging the autopilot

To engage the autopilot:
- Select the engage button to activate last active mode
- Select the mode button to display the list of available modes, then select the preferred mode

The autopilot will engage in the selected mode, and the autopilot controller will change to show active mode options.

To disengage the autopilot:
- Select the standby button

When the autopilot is in standby, the boat must be steered manually.

Anchor modes

In these modes the trolling motor maintains the vessel position at a selected location.

➔ **Note:** When in anchor mode, the vessel heading can be affected by wind or current.

The following anchor options are available:

Change the position in anchor mode

Use the arrow buttons to reposition the vessel when in anchor mode. Each press on a button will move the anchor position 1.5 m (5 ft) in the selected direction.
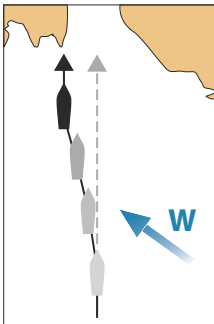
Heading lock mode

In this mode the autopilot steers the vessel on the set heading.

When the mode is activated, the autopilot selects the current compass heading as the set heading.

→ **Note:** In this mode the autopilot does not compensate for any drifting caused by current and/or wind (**W**).

To change the set heading

An immediate heading change takes place. The heading is maintained until a new heading is set.

NAV mode

> ⚠ Warning: NAV mode should only be used in open waters.

Prior to entering NAV mode you must be navigating a route or towards a waypoint.

In NAV mode the autopilot automatically steers the vessel to a specific waypoint location, or along a pre-defined route. Position information is used to change the course to steer to keep the vessel on the track line and to the destination waypoint.

When arriving at the destination, the autopilot switches to the selected arrival mode. It is important to select an arrival mode that fits your navigation needs before NAV mode is activated. Refer to *"Arrival mode"* on page 9.

NAV mode options

While in NAV mode the following buttons are available in the autopilot controller:

Restart
Restarts the navigation from the vessel's current position.

Skip
Skips the active waypoint and steers towards the next waypoint. This option is only available when navigating a route with more than one waypoint between the vessel position and the end of the route.

Turn pattern steering

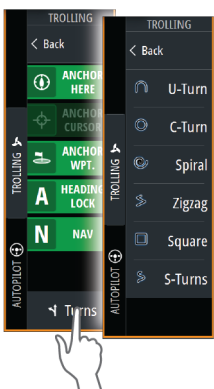The system includes a number of automatic turn steering features.

When a turn pattern is activated, the system creates temporary waypoints on the turn.
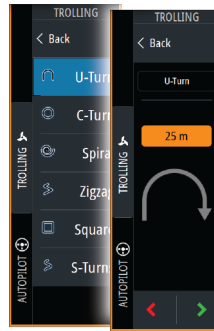
The last waypoint on the turn is the final waypoint. When the vessel reaches the final waypoint, the vessel goes into arrival mode. Refer to *"Arrival mode"* on page 9.
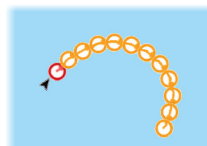
Starting a turn

• Select the port or starboard button

Turn variables

All turn patters have settings that you can adjust before you start a turn, or at any time when the boat is in a turn.

U-turn

Changes the current set heading by 180°.

Turn variable:

- Turn radius

C-turn

Steers the vessel in a circle.

Turn variable:

- Turn radius
- Degrees to turn

Spiral

Makes the vessel turn in a spiral with a decreasing or increasing radius.

Turn variables:

- Initial radius
- Radius change per loop
- Number of loops

Zigzag-turn

Steers the vessel in a zigzag pattern.

Turn variables:

- Course change per leg
- Leg distance
- Number of legs

Square

Steers the vessel in a square pattern, doing 90° course changes.

Turn variable:

- Leg distance
- Number of legs

S-turn

Makes the vessel yaw around the main heading.

Turn variables:

- Turn radius
- Course change
- Number of legs

Trolling motor speed control

In Heading lock mode, Nav. mode and in Turn pattern steering the autopilot system can control the trolling motor speed.

The set target speed is displayed in the autopilot controller.

There are two ways to control the target speed of the trolling motor:

- Propeller rate, set as a percentage of power (**A**)
- Cruise control speed (**B**)

Switch between the speed options by selecting the speed icon.

The speed is increased/decreased in preset steps by selecting the plus and minus buttons. The speed can also be set manually by selecting the speed field (**C**).

Autopilot settings

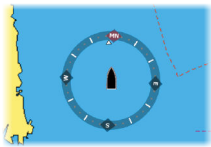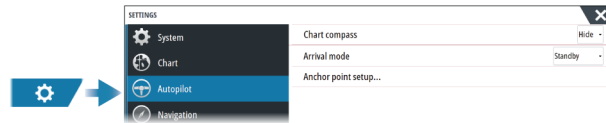The options in the Autopilot settings dialog can vary.

Chart compass

Select to display a compass symbol around your boat on the chart panel. The compass symbol is off when the cursor is active on the panel.

Select active autopilot

Selects if the autopilot controls the trolling motor or the outboard motor(s).

Auto hide autopilot bar

Controls whether the autopilot information bar is shown when the autopilot is in standby.

Arrival mode

The autopilot switches from navigation mode to the selected arrival mode when the vessel reaches the destination point.

Standby

Disengages the autopilot. The trolling motor is controlled by hand-held remote or by foot pedal.

#### Heading lock

Locks and maintains the last vessel heading.

Anchor

Anchors the vessel at the destination point.

Anchor point setup

The trolling motor can store a number of anchor points, labelled with MTG prefix. Anchor points in the trolling motor are displayed in the Anchor point dialog.

These MTG anchor points can be saved as a waypoint in the MFD system. The position of an MTG anchor point can be redefined to be identical to an existing waypoint, or to the current vessel position.
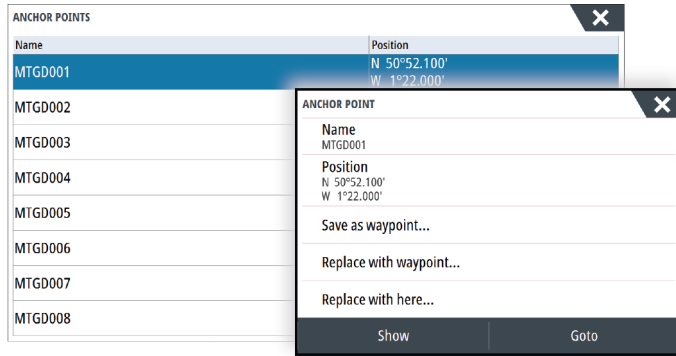
Configure the Ghost trolling motor foot pedal keys

You can configure three of the actions keys (**A**, **B** and **C**) on the Ghost series trolling motor foot pedal.
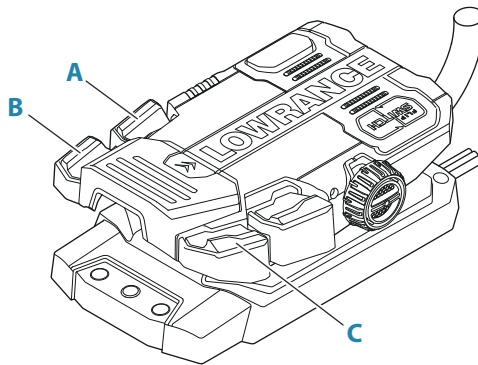
Select an action from the drop-down list for each of the keys you want to configure.