

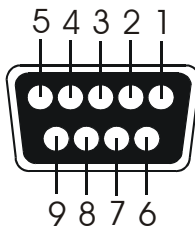
## Default Settings

Port	Baud Rate	Interface Level	Wire pair	NMEA Messages	Update Rate
Primary Port A	19200	RS-232C	Blue(TX) / Black (RX)	GGA, GSV, VTG, ZDA, HDT, ROT	1 Hz
		RS-422 (output only)	Green(+) / Black(-)		
Primary Port B	19200	RS-232C (output only)	White (TX)	GGA, GSV, VTG, ZDA, HDT, ROT	1 Hz
		RS-422 (output only)	Yellow(+) / Black(-)		
Secondary Port A	19200	RS-232C	Brown(TX) / Black (RX)	No output (idle)	N/A

- Unpack the system and ensure the order is complete by comparing the parts received to the packing slip
- Choose a location for installation using either the pole or fixed mount where the Vector is:
  - Away from other antennas and electrical equipment
  - No structures above the horizon
  - Along the centerline of the boat with arrow on underside pointing towards the bow.
  - Horizontal

*\*Connect the power/data cable before fastening on the mount*

- Connect power source of 8 to 40 VDC
- Connect DB9 to unterminated wires of Vector data/power cable for communication with external equipment or COM port of computer. It is recommended that you use the output of position and heading from the Primary receiver, either from Port A or B. Both Ports may be configured through Port A, the connections for which are detailed below:



Pin	Wire Color	Signal
2	Blue	Primary Port A, RS-232 Transmit
3	Black twisted with blue	Primary Port A, RS-232 Receive
5	Black twisted with white	Signal Ground

- Connect to COM port for additional configuration requirements using a terminal program or PocketMAX PC. Use default baud rate of 19,200 bps and 8-N-1 protocol.
  - Change baud rate of either port to match that of the external equipment to which the Vector will be connected. After the baud rate is changed you will need to close the terminal program and reconnect at the speed selected. Available baud rates are: 4800, 9600, 19200 or 38400
  - Configure NMEA messages to be output on appropriate port
  - Select differential source. Default is SBAS (WAAS/EGNOS), but BEACON may be selected on PRO model
  - Input heading bias (-180° to +180°) to compensate for any offset from the centerline
    - If placing antennas crosswise, add heading bias and also configure to output roll rather than pitch
  - Input bias for pitch or roll (-15° to +15°) to compensate for any offset from horizontal
  - Enable supplementary sensors (Default is only TILTAID enabled)
  - When finished, save configuration changes using \$JSAVE command

	<b>GYROAID</b>	<b>TILTAID</b>	<b>MAGAID</b>
<b>Recommended</b>	YES	YES	*Only if precisely calibrated, and in stable magnetic environment
<b>Purpose</b>	When GPS lock is lost: - Provides alternate source of heading for up to 3 minutes - Shortens heading reacquisition time	Reduces startup and reacquisition times for obtaining heading	Reduces startup and reacquisition times for obtaining heading  Provides alternate heading when GPS unavailable
<b>Calibration Procedure</b>	Will self-calibrate after several minutes  To manually calibrate: -After heading is computed -\$JATT,GYROAID,YES -Spin Vector for 1 minute at less than 15° per second -Leave unit stationary for 4 minutes **Needs to be recalibrated if power turned OFF	Precalibrated during manufacture  To recalibrate: -Ensure Vector is level -\$JATT,TILTCAL	Enable magnetometer \$JATT,MAGAID,YES  Clear current setting \$JATT,MAGCLR  -leave alone to self-calibrate, which may take several days OR -spin 360° 3 to 10 times  check calibration with \$JATT,MAGCAL