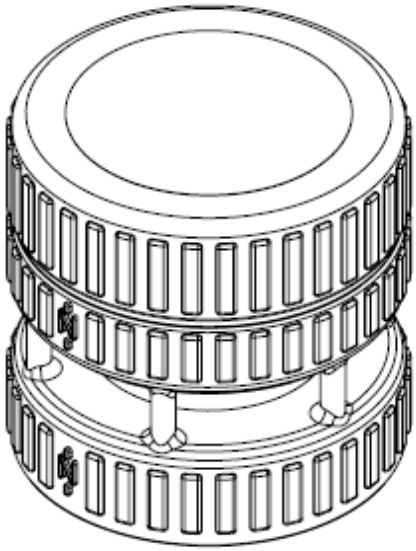
FT205EV™ – Digital Wind Sensor User Manual

Surface and Pole Mount Options

Digital RS422, RS485HD and UART options



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Contents

Product Symbols

The following symbols may be used upon the product and within the manual.

Meaning / Description	Symbol	Signification / Description
Warning/ Caution An appropriate safety instruction should be followed or caution to a potential hazard exists		**Avertissement / Attention** Une instruction de sécurité doit être suivie ou attention portée à un danger potentiel qui existe.
DC Current only Equipment operates under Direct Current (DC) supply only.		**Courant continu uniquement** L'équipement fonctionne sous une alimentation en courant continu (CC) uniquement.
Product Disposal In accordance with European directive 2012/19/EU on Waste Electrical and Electronic Equipment (WEEE), these product components must be recycled. This should be done by returning the product to FT Technologies or by using an appropriate waste disposal company. This product should not be disposed of in general waste of landfill. This product complies with the RoHS2 (2011/65/EU) directive.		**Élimination du produit** Conformément à la directive européenne 2012/19/EU relative aux déchets d'équipements électriques et électroniques (DEEE), ces composants du produit doivent être recyclés. Cela doit être fait par le retour du produit à FT Technologies ou en utilisant une entreprise d'élimination de déchets. Ce produit ne doit pas être éliminé avec les ordures ménagères ou en décharge. Ce produit est conforme à la directive RoHS2 (2011/65/EU).
CE Mark The EU Declaration of Conformity complies with the essential requirements of the following applicable EMC Directive 2014/30/EU, and carries the CE Marking accordingly.		**Marquage CE** Déclaration de conformité CE de la compatibilité électromagnétique (EMC) et marquage CE conformément à la directive CE 2014/30/EU.

Safety Instructions

English

- To ensure the safe installation and operation of this product the equipment must be installed and integrated:
    - Using suitably qualified and trained personnel
    - In accordance with any regional electrical codes
    - In accordance with the instructions set out in this manual, observing all information, warnings and instructions
    - In accordance with any other instructions or guidance FT Technologies provide
    - Following applicable regional safety standards
- To ensure that the product remains compliant with electrical safety requirements it should be:
    - Connected to an appropriately approved isolated power supply, rated 6-30VDC and be current limited (0.2A Maximum)
    - Protected by surge protection devices
    - Connected using an appropriate interface cable
- The equipment must only be operated within the range of the specified technical data and used for the purposes for which it was designed.
- The equipment should always be transported in packaging which is appropriate, that will prevent any accidental damage from occurring.
- Always ensure that any failures or errors from the product cannot cause any damage to any other equipment or property or cause any other consequential effects.

1 INTRODUCTION

1.1 Product Overview

The FT205EV is the first in a new generation of lightweight ultrasonic wind sensors. It has a unique combination of low weight (100g) and a wind speed range up to 75m/s.

The FT205EV (Evaluation Version) features a graphite and nylon composite body. The light weight of the FT205EV together with the proven FT Acu-Res® technology make it ideal for use on aerial drones and other weight-critical applications. It has low levels of electrical emissions and is highly resistant to interference from vehicle systems. During development the sensor has been HALT ('highly accelerated life test') tested up to 60G demonstrating its operational strength.

The FT205EV allows configurable RS422 (full-duplex), RS485 (half-duplex) or buffered UART (full-duplex) communication outputs (3V and 5V TTL compatibility). It has been designed for easy integration and uses a Molex CLIK-Mate connector (Molex part number: 505405-0860). The sensor is provided with a 600mm cable (Molex part number 15135-0806).

1.2 Build Versions and Labelling

Figure 1 shows the sensor label which includes sensor serial number and relevant user information:

Figure 1: Sensor Label

The main sensor label also includes relevant user information and regulatory symbols.

1.3 Scope of Use

The FT205 sensor has been designed primarily for wind reference use on UAV drone systems. Due to its lack of metallic body and heater, it may not be suitable for long-term, high-reliability operation, particularly during periods of bad weather.

No promise in part or full can be given to guarantee a sensor's continuous operation, as circumstances can occur that may result in the failure of the output from a sensor. Circumstances can include:

- Poor installation
- Inadequate inspection
- Power supply failures
- Poor quality electrical connections
- Lightning exposure
- Problematic environmental conditions (rain, snow, icing, cold-temperature etc.)
- Physical Damage

Higher levels of wind speed and wind direction data availability are achieved through the use of an additional FT sensor or alternative sensor. Control strategies or algorithms, which compensate in whole or in part, for any temporary interruption of data from individual sensors should also be applied. The choice and implementation of such methods is entirely the Purchaser's responsibility.

1.4 Disclaimers

There are no warranties, representations or conditions, expressed or implied of any kind given in this manual for any design application. The Purchaser should independently undertake sufficient testing to confirm validity and suitability of any design. The Purchaser assumes all risks and liability in conjunction with the use of the information given.

Any warranty given by FT Technologies in respect of the Equipment is conditional upon the sensor being handled, installed, integrated and operated in accordance within the guidelines given in this manual.

FT Technologies can take no responsibility for the effectiveness of any sensor lightning protection scheme implemented. The wind sensor has passed a wide range of EMC tests, but FT Technologies does not warrant the sensor to survive lightning strikes.

Information supplied by FT Technologies Ltd. shall not be construed as permission to license to operate under, or recommendation to infringe any existing or pending patent, patent applications or trademarks.

FT Technologies reserves the right to change product specifications, designs and functionality without notice or obligation.

The FT205EV lightweight wind sensor comes with a limited 12-month warranty. FT will replace an FT205EV sensor that fails within 12 months of despatch due to a failure of electronic components or poor manufacture. This warranty does not cover failure resulting from mechanical damage or damage from lightning.

2 FUNCTIONAL DESCRIPTION

2.1 Technical Performance

Sensor Performance[1]

Measurement Principle	Acoustic Resonance (compensated against variations in temperature, pressure and humidity)
Wind Speed Measurement	
Range	0-75 m/s (0-270 km/h, 0-145.8 knots)
Resolution	0.1 m/s
Accuracy	±0.3 m/s (0-16 m/s) ±2% (16 m/s-40 m/s) ±4% (40 m/s-75 m/s)
Wind Direction Measurement	
Range	0 to 360°
Sensor Accuracy	4° RMS
Compass Accuracy[2]	5° RMS
Resolution	1°
Acoustic Temperature Measurement[3]	
Units	Celsius, Fahrenheit or Kelvin
Resolution	0.1°
Accuracy	±2°C under the following conditions: Wind speed between 5m/s and 60m/s Temperature Difference < 10°C (Sensor Temp. vs Air Temp.) Operating (air) temperature between -20°C and +60°C
Environment	
Temperature Range	-20° to +70°C (operational) -40° to +85°C (storage)
Humidity	0-100%
Altitude	0-4000m

Data I/O

Interface options:	RS422 (full-duplex) RS485 (half-duplex) Buffered UART full-duplex (3V & 5V TTL compatible)
Format	ASCII ‘Polled’ or ‘Continuous Update’, Polar and NMEA 0183
Data Update Rate	Up to 10 measurements per second (10 Hz)

Power Requirements[4]

Supply Voltage	6-30 VDC range (24 VDC nominal)
Sensor Current	30mA typical

Physical

Weight	100 g
External Body Material	Nylon and graphite composite
I/O Connector	Molex CLIK-Mate (Molex part 505405-0860)
I/O Cable	Molex CLIK-Mate (Molex 600mm part 15135-0806)
Mounting Method	Surface-Mount (adaptor available for pipe-mounting)

Notes:

1. All specifications subject to change without notice. Specifications calculated with the default settings and filters enabled
2. Requires user calibration (see Section 2.5)
3. See Sections 2.9, 6.4.2 to 6.4.4 for further details
4. See safety instruction requirements (page 5). A suitable PSU capable of providing up to 0.2A maximum is recommended. RS422 current load is dependent on topology and resistor values, RS422 in ‘always enabled’ mode may draw higher currents. See Section 5.2 for RS422 power requirement details

2.2 Wind Speed Calibration

The wind sensor is calibrated in our wind tunnels before dispatch. As the sensor has no moving parts, there is no need to recalibrate a sensor over its lifetime as no measurement degradation will occur. The sensor's compact strong monolithic shape is designed to prevent accidental transducer movement or damage. FT Technologies' calibration procedure and wind tunnels are designed to give a calibration profile that is within the accuracy limits set in the product technical specification (see Section 2.1). Periodically the accuracy of FT's wind tunnels are compared with the accuracy of an independent wind tunnel to ensure that no drift has occurred.

In exceptional circumstances users may wish to apply additional calibration factors. The sensors have an option to set a User Calibration Table, which can modify the wind sensor's wind speed output (see Section 6.4.23).

The User Calibration Table can be programmed with up to 64 correction factors which are maintained in non-volatile memory. When enabled, the uncorrected wind speed output is adjusted according to the stored User Calibration Table records using linear interpolation. The adjustments are applied to wind speed readings regardless of wind direction.

2.3 Wind Speed and Direction Filtering

It is important that the system does not rely exclusively on a single wind reading for any control decision. A single reading may be inaccurate due to measurement error, turbulence, corruption or interference. It is recommended that an average of wind readings is used. In addition if 100% data availability is required then a second FT sensor or alternative wind sensors should be fitted in addition.

The sensor has optional internal filtering available. This is a digital finite impulse response (FIR) filter, which works by calculating the moving average of a fixed number of previous readings. If filtering is being applied externally, the sensor's output filters can be disabled. If filtering inside the sensor is preferred, the length of the averaging for both wind speed and direction can be independently set (See Sections 6.4.13 and 6.4.14).

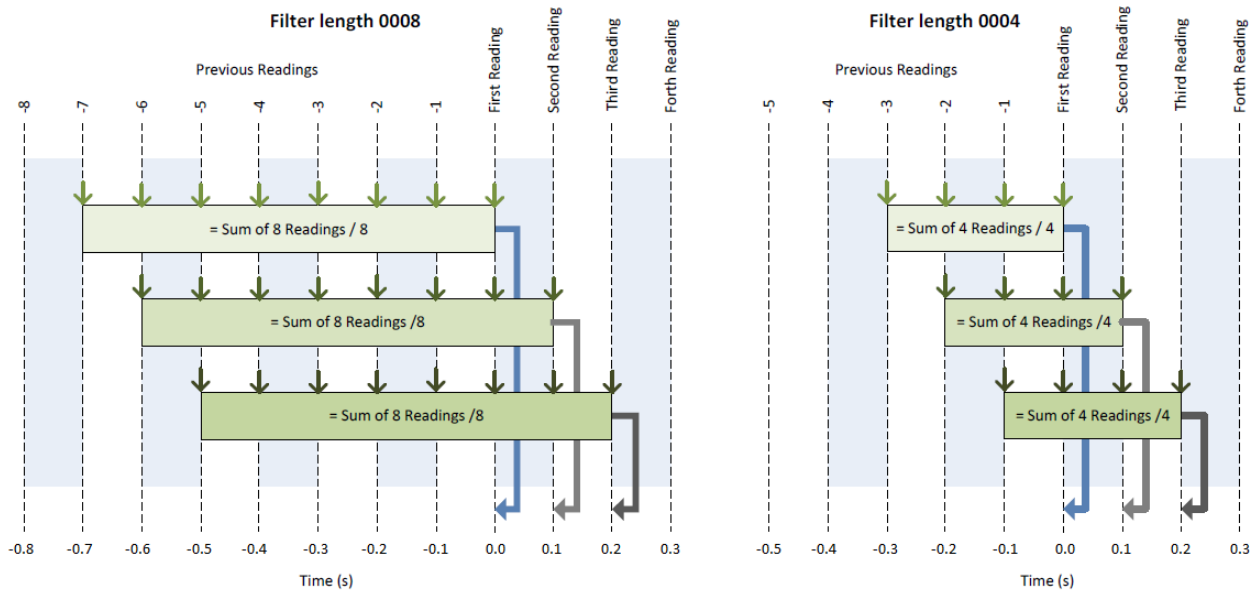


Figure 2: Examples of FIR Filtering

It is recommended to use average readings to reduce the effects of air turbulence.

2.4 Electronically Offsetting the Wind Direction Datum

For applications where the compass is not being used, the wind direction datum can be ‘electronically’ rotated using the CF command. The declination angle function normally used in conjunction with the compass function can be used to realign the datum position anywhere in the range 0-359.9°.

See Section 6.4.6 for further details.

2.5 Compass & Declination Angle Operation

The FT205EV is fitted with a solid-state electronic compass so that the wind direction can be measured relative to magnetic North if required.

Since the FT205EV is intended for system integration it is necessary to calibrate the compass before operation and testing is recommended. Refer to Section 6.4.6 for calibration software commands. Enabling the compass will require approximately 5mA of additional current draw.

The wind direction can be measured either relative to magnetic North, or by programming the sensor with the geographical location declination angle, relative to true North. The compass function can also be disabled if required so that the wind direction is measured relative to the datum mark on the wind sensor body (as per Figure 8). The compass heading can also be read back at any time using the CF command. See Section 6.4.6 for full details of the CF command. Both the Polar format (P) and NMEA 0183 format (N) outputs provide wind direction data relative to North (if the compass function is enabled). The NMEA 0183 message also has a field that indicates whether the compass module is enabled or disabled.

The effects of fixed local magnetic fields (i.e. those caused by magnetised ferrous material in proximity to the compass) can be compensated for by performing an in situ compass calibration. It is important that the calibration is performed with the FT205EV mounted in its final position within the host system. The calibration can only compensate for fixed magnetic fields generated by the host system. Varying fields caused, for example, by ferrous objects passing near the FT205EV (say by a car or truck) or high current electric circuits will not be corrected. Should the magnetic signature of the host system change significantly (because component parts have been added or removed), then a recalibration may be required.

2.5.1 Compass Calibration

Compass calibration should be performed away from any external stray magnetic fields. To calibrate the FT205EV compass proceed as follows:

1) Mount the FT205EV in its final position within the host system

2) Ensure the compass is enabled (send the CFE ‘enable compass’ command, see Section 6.4.6).

3) Send the CFC ‘enable calibration’ command (see Section 6.4.6). Important: No further commands should be sent to the FT205EV after the CFC command has been sent.

4) Slowly rotate the host system 1 complete revolution in the horizontal plane. The revolution should take between 40 and 60 seconds.

5) To complete the calibration send the CFE ‘enable compass’ command (see Section 6.4.6).

6) Store the new calibration Parameters in the compass module using the CFMS command. The save command, for example $01,CFMS*//<cr><lf>, will save the new compass calibration parameters calculated during the calibration process to the Interface Board Flash memory. This command is required.

2.6 Selective Filter Scheme

In addition to the averaging filter described in Section 2.3, the sensor has a feature called the Selective Filter. The scheme allows the user to set a “validity period”, during which the sensor will exclude invalid readings from entering the averaging filter. The output will freeze on the last previous “good” reading and only raise an error flag once the number of bad readings exceeds the validity period. This scheme can be enabled by factory configuration or by using the FL command (see Section 6.4.15). The filter is turned off by default to match legacy behaviour.

2.7 Error Detection

The sensor has a self-checking mechanism which can detect if a reading is invalid. On very rare occasions where an invalid reading may have been detected, this is signalled to the computer or data logger by setting an error flag character within the wind velocity output message (see Sections 6.4.29 and 6.4.30).

When an error is detected, the error flag character is set to a value of: 1.

Note: An optional Overspeed Warning Scheme can be enabled (but is disabled by default). See Section 2.8 for further details.

It is important that error flags are not ignored. Data associated with an error flag should **not** be processed as valid wind data. The system should be capable of riding through rare periods when data may be temporarily unavailable. If errors are ongoing (more than several seconds), a reset of the sensor should be applied (see Section 6.4.20 for instructions on sending an RSU command).

It is recommended that errors are monitored and logged. If the frequency of errors has recently increased, then inspection of the sensor for physical blockages may be required (see Section 4.1).

2.8 Overspeed Warning Scheme

During periods where the sensor detects wind speed beyond the rating of the sensor, the sensor will (by default) indicate a general error flag status.

An additional overspeed warning scheme can be enabled: if an overspeed condition is detected (above the highest speed rating), the error flag character will be set to: 2 (see Sections 6.4.29 and 6.4.30) unless a general error condition is also detected and the flag will be set to 1.

This scheme is disabled by default.

The Overspeed Warning Scheme can be enabled by software commands (see Section 6.4.19), via the Acu Vis PC software program or enabled in the factory before despatch.

2.9 Acoustic Temperature

The Acoustic Temperature feature takes a measurement of the ambient temperature via measurable acoustic properties of the airflow. Sections 6.4.2 to 6.4.4 describe related software commands.

Averaged data should be used. The averaging system can be performed for 0 to 50 seconds (in increments of 10 seconds), or between 1 to 10 minutes (in increments of 1 minute).

See Section 2.1 for details regarding operating specifications. Operation with high temperature gradients (between sensor body and ambient airflow), extreme humidity levels and low wind conditions (below 5m/s) may result in reduced accuracy.

Caution: The acoustic temperature feature requires calibration at FT Technologies. If the sensor has had a software upgrade to 7.5 (or above) then the data will be uncalibrated and may not comply with the official specification.

3 MECHANICAL & ELECTRICAL INSTALLATION

The FT205EV is surface-mounted and optimised for lightweight operation. The sensor uses a Molex Clik-mate PCB connector (part 505405-0860) and is supplied with a 600mm cable (various lengths available from Molex, 600mm cable part 15135-0806). An adaptor is available and included with the sensor for pipe-mount installation.

Water resistance is achieved using a compression-fit foam gasket secured with M3 screws. The water resistance is validated using rain tunnel tests at 2.5m of rain per hour using the supplied fixings. The sensor weighs 100g and the external body material is 3D printed using a graphite and nylon composite.

The surface mount option uses a foam gasket and 3x M3 screws for assembly. Adaptor accessories for pipe-mount installation are included consisting of a base unit, adaptor, 2x foam gaskets and 6x M3 screws. The pipe section (Ø 20) is not supplied by FT due to variable customer requirements. The intended bonding scheme for the pipe is using an epoxy adhesive. Due consideration is required for sensor placement due to the spinning rotors.

Note: the length of the M3 screws will be dependent on the thickness of the integrated system mount.

Ensure the airflow into the sensor is not obstructed or influenced by nearby objects.

- See the safety instruction requirements on page 5
- The wind sensor installation must be properly designed to ensure the correct operation of the sensor. This section is for guidance only. It is the responsibility of the designer and installer to ensure that the installation and its design is fit for purpose. Please see Disclaimer Section 1.4
- Caution – Excessive length or tightening of the M3 screw may cause damage to the sensor and threads

3.1 FT205EV Sensors

3.1.1 Mechanical & Electrical Integration

The sensor measures the effects of airflow through the sensor cavity on a resonating acoustic signal. The sensor can be rotated to ensure alignment with a standard reference, typically Magnetic North, or the integrated compass can calculate this automatically. For angular alignment a North datum feature is marked on the sensor with an ‘N’, when the wind blows towards the N the sensor reports 0° (unless the compass feature is enabled).

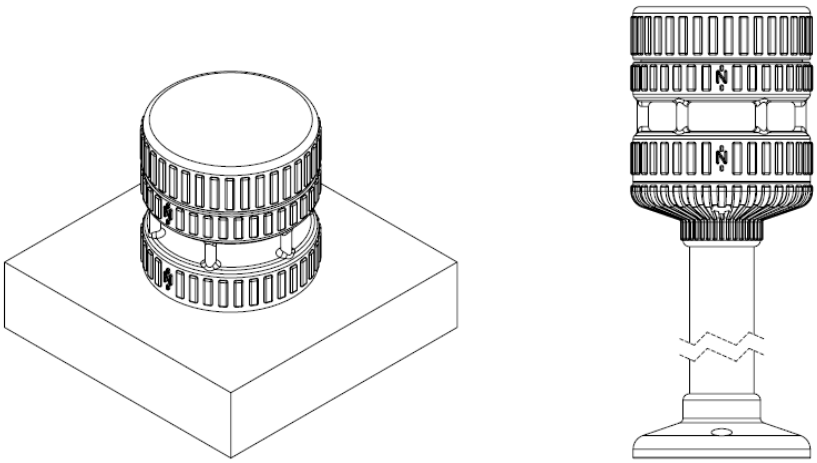


Figure 3: The FT205EV Sensor – Mounting Examples

The mounting surface should be smooth and flat. Textured, uneven or damaged surfaces will reduce the quality of the water ingress protection.

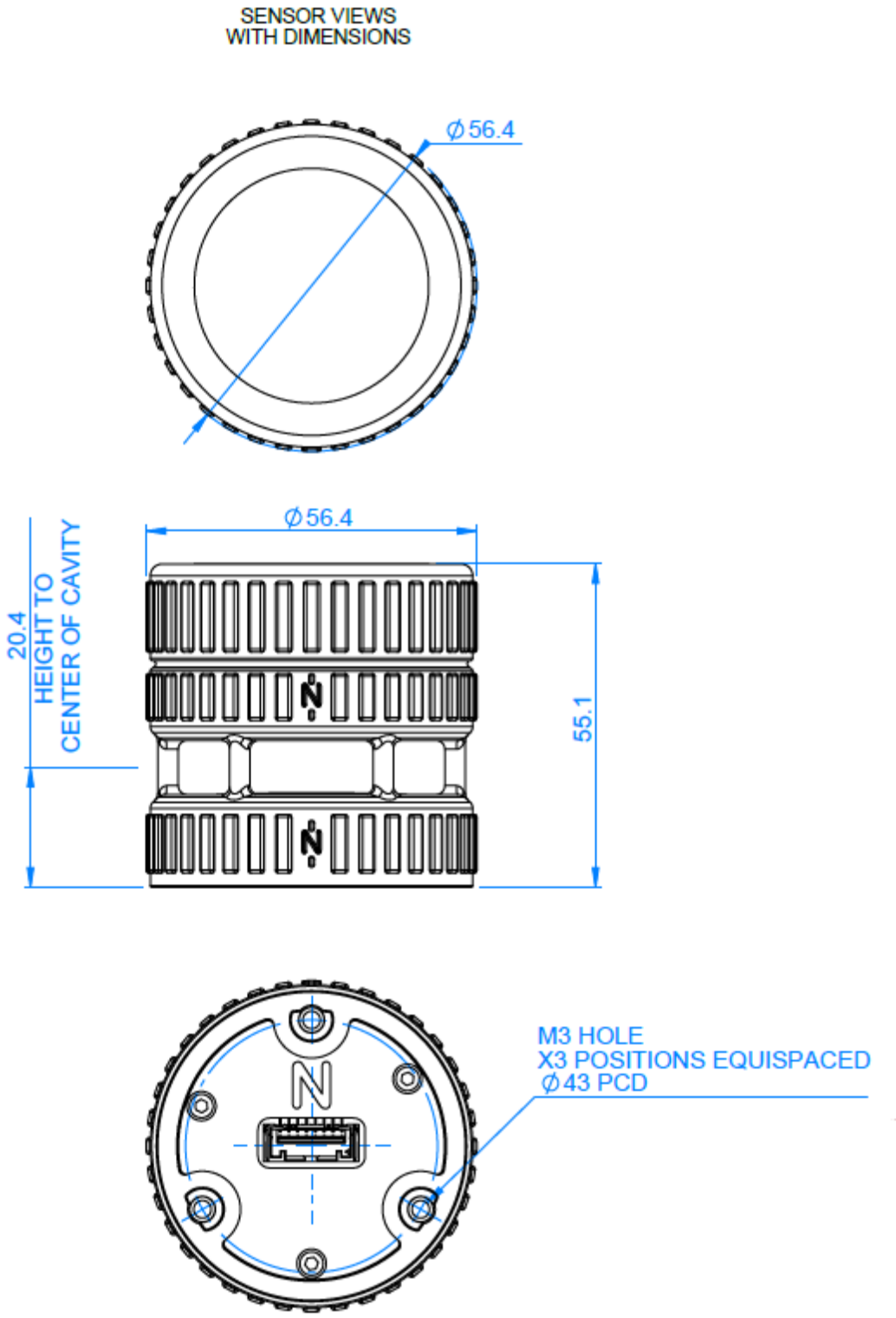


Figure 4: FT205EV Sensor – General Sensor Views (units in mm)

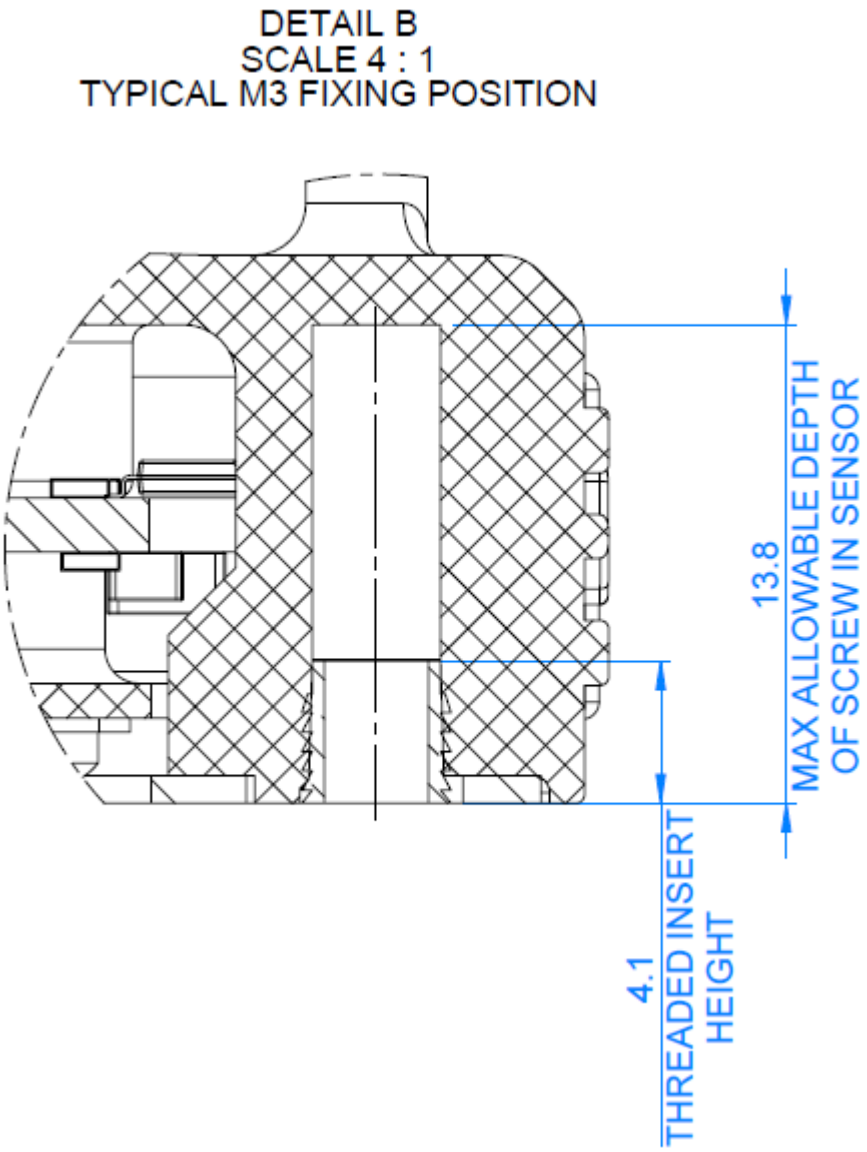
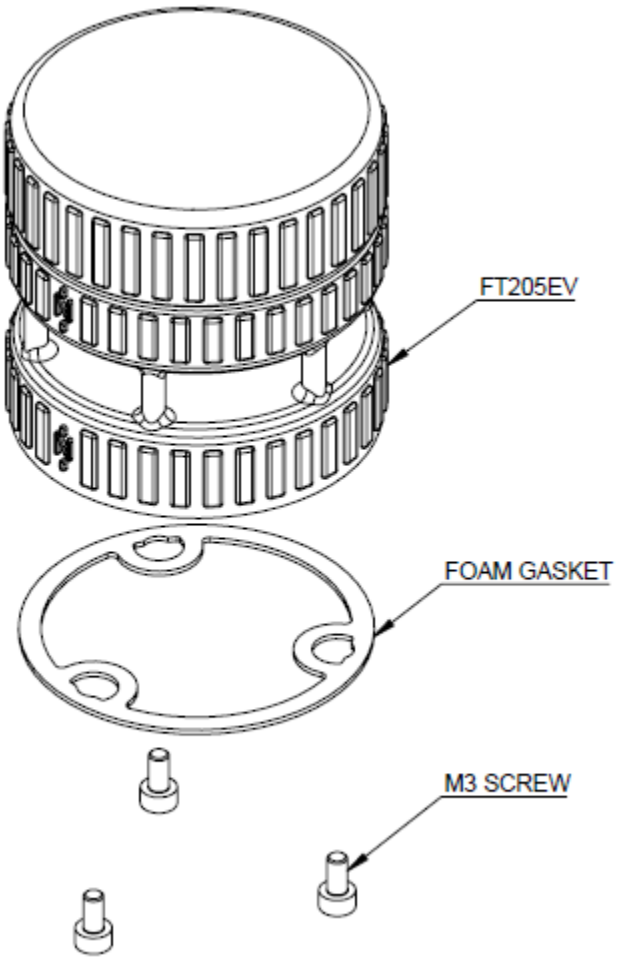


Figure 5: FT205EV Sensor - M3 Thread Details

Caution – Excessive length or tightening of the M3 screw may cause damage to the sensor and threads.



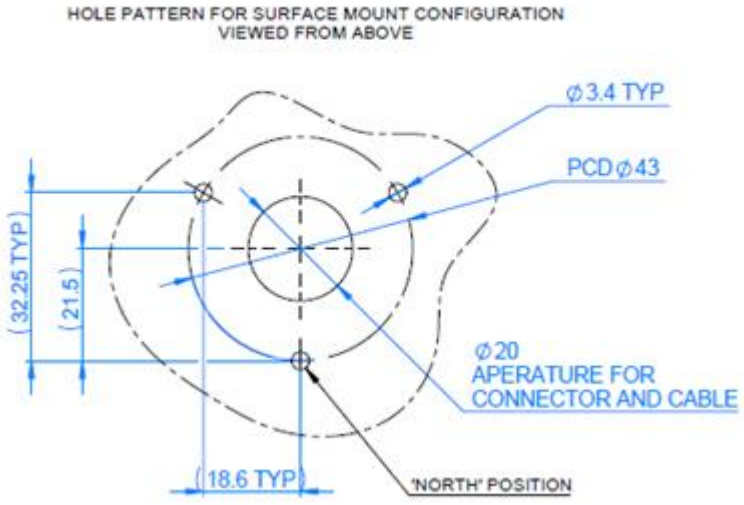


Figure 6: FT205EV – Surface Mount Option

Caution – Excessive length or tightening of the M3 screw may cause damage to the sensor and threads.

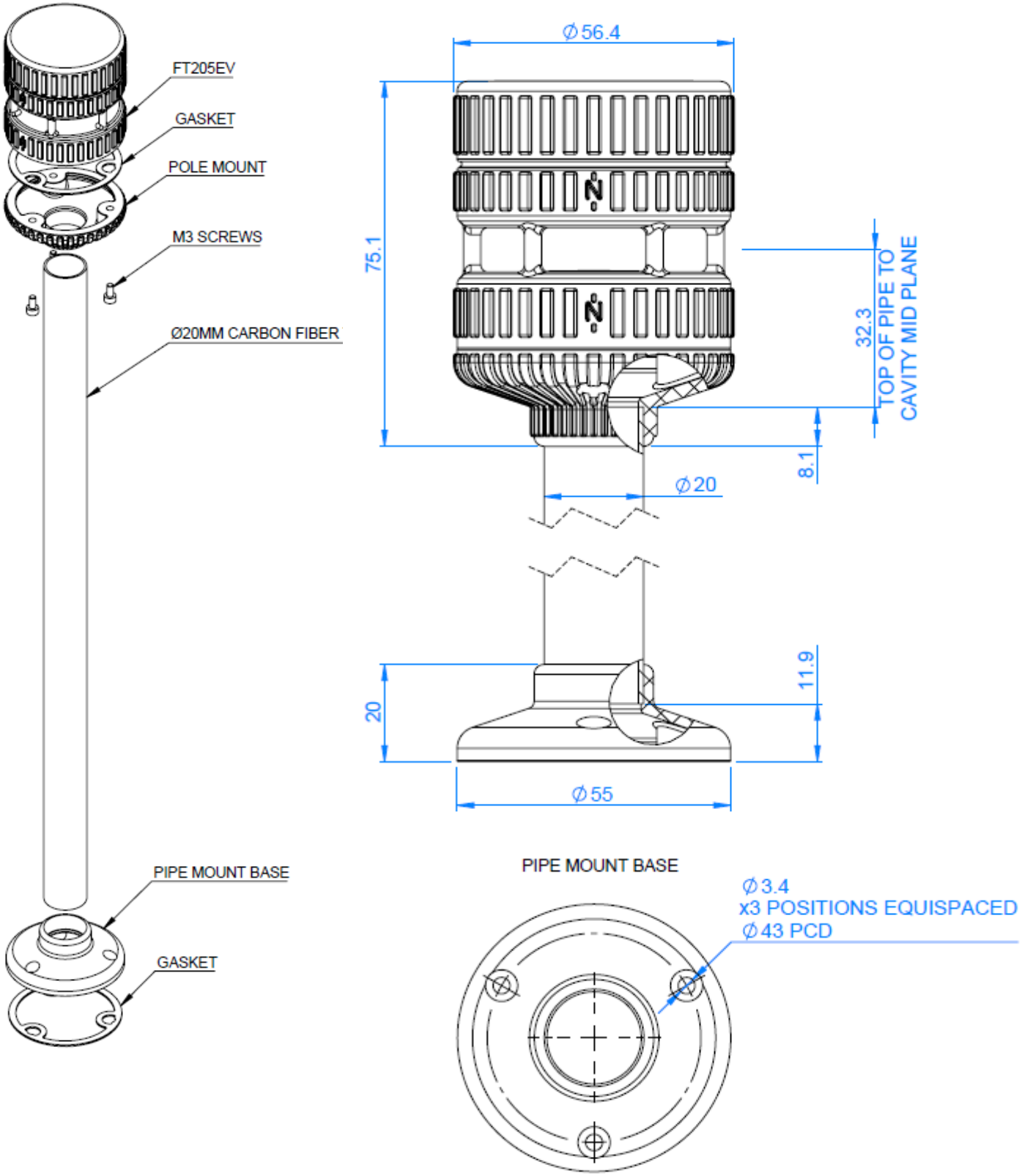


Figure 7: FT205EV – Pipe-Mounted Option

When the pipe mounted version is used it will be necessary to source an appropriate length of cable.

The user selection of pipe material depends on user requirements, the FT recommended material is carbon fibre due to its low weight and high rigidity.

Warning: The user should review all aspects of the pipe material and bonding/adhesive structure to ensure it is compatible with health and safety requirements.

Caution – Excessive length or tightening of the M3 screw may cause damage to the sensor and threads.

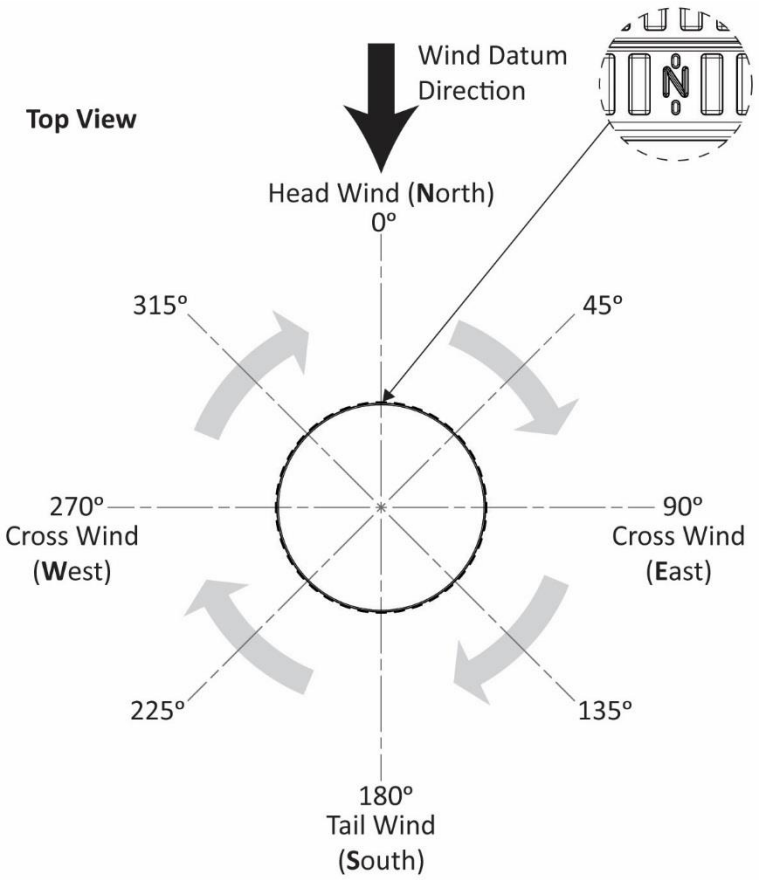
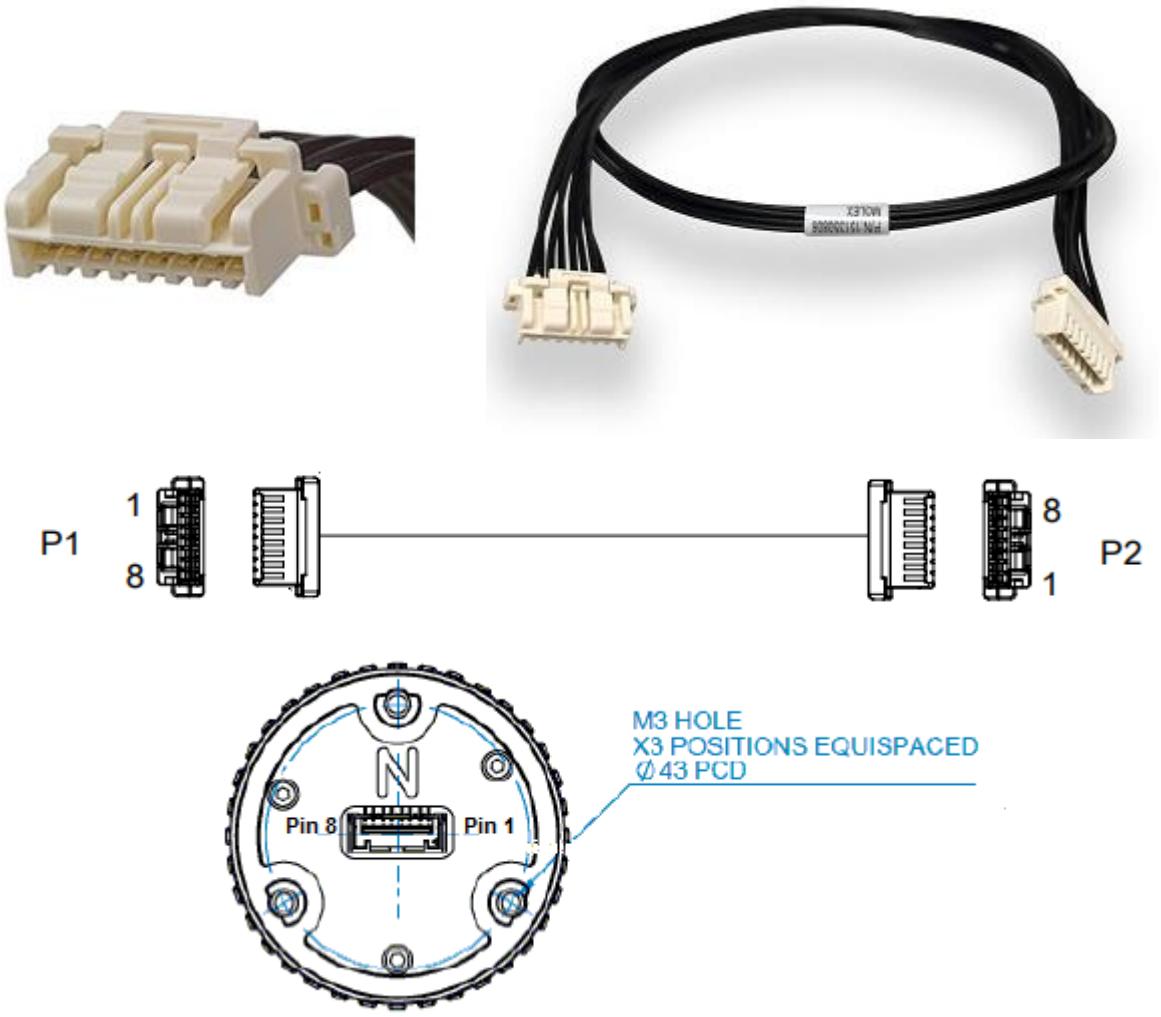


Figure 8: Wind Direction Reference (Compass Disabled)

3.1.2 Connector Details

The FT205EV sensor uses the Molex CLIK-Mate 8-way single-row connector (Molex part 505405-0860). The sensor is provided with 1x 600mm cable length (50-600mm lengths are available from Molex). The 600mm cable length has the Molex part number 151350806. The cables are fitted with the same connector on both cable ends and corresponding pin numbering. The connector is keyed and can only be inserted in the correct orientation.



(not to scale)

Pin	RS422 (full-duplex)	RS485 (half-duplex)	Buffered UART (full-duplex)	Molex Wire Colour
1	Ground			Black
2	6-30 VDC			
3	RS422_A RX (-)	RS485_A (-)		
4	RS422_B RX (+)	RS485_B (+)		
5	RS422_A TX (-)			
6	RS422_B TX (+)			
7			UART_RX	
8			UART_TX	

Figure 9: Sensor Connector (above), Cable (below) and Wiring Diagram

Care must be taken to ensure that the cable is suitable for the environment it will be used in and is adequately rated and approved. Shielding and the use of EMI conduit may be necessary.

The sensor has reverse polarity protection and is protected against miswiring of the intended cable and the power supply rating. The cables are not shielded and EMI consideration is recommended.

3.1.3 Surge & EMI Protection

It is important to install the sensor and cabling with appropriate surge and EMI protection.

All connections from the wind sensor to any data acquisition equipment and power supply should run through suitable Surge Protection Devices (SPD). This will suppress unwanted overvoltage transients present on the signal or power lines. The surge suppression devices should conform to an appropriate standard (for example UL 1449 listed).

This sensor is designed for lightweight applications and does not have the enhanced surge/lightning protection of advanced industrial sensors within the FT7 range.

4 SERVICE, CONFIGURATION & TESTING

4.1 Inspection

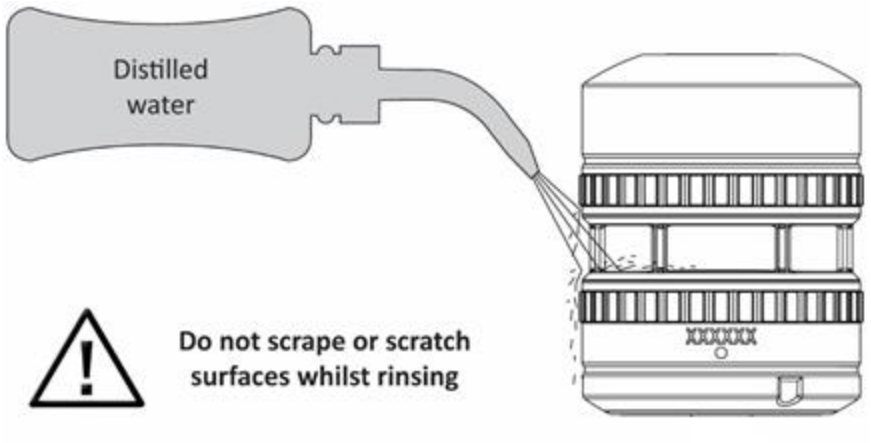
The following checks are required to identify any signs of corrosion or damage on the sensor which may hinder its performance. It is recommended that these checks be carried out annually.

Mechanical damage: Check the sensor body for signs of damage, paying attention to the seals. Also inspect for signs of lightning damage which may appear as burns or scorch marks (or burnt smells). If damage has occurred replace the sensor immediately. Inspect the cavity for wear, corrosion and damage. Check the gasket, fasteners and accessories are in good condition, replace them if necessary.

Corrosion: Inspect the mounting surfaces of the sensor for signs of corrosion. If corrosion is present on any external mounting surface, it should be removed using an abrasive cloth. Check that any seals and fasteners are in good condition and tighten as necessary. If corrosion is present replace with parts of an appropriate finish (see Section 3).

Interconnection cable: Inspect the condition of the cable. If it has become frayed or damaged it should be replaced. Intermittent cable faults may not be visible and may show up as data errors. Check the intended network component values (termination resistors etc.).

Connector protective sleeve: If cable protection is used, check for any signs of damage or degradation.



Cleaning: If any debris is present this can be removed by gently rinsing the measurement cavity surface with distilled water using a laboratory wash bottle or similar. Please note excess water droplets can be removed by lightly blowing or shaking the sensor.

Do not scrape or scratch the surfaces whilst rinsing. **Under no circumstances** should objects be inserted inside the measurement cavity, as this can cause irreparable damage. The body of the sensor can be washed if required

using the same method as described above. When washing the sensor care must be taken to avoid water ingress to the connector at the base of the sensor or into attached permeable systems.

Do not use cleaning chemicals to clean the sensor. If washing a nearby item protect the sensor with a suitable cover. Ensure the cover is removed before re-enabling the wind data survey.

4.2 Fault Finding & Troubleshooting

To determine whether a sensor has a fault carry out the following steps:

- Follow the inspection procedure above to identify signs of physical damage.
- Remove any objects or insects lining the cavity or blocking the airflow.
- Reset the sensor (RSU command or power-cycle).

If there are signs of physical damage and/or the sensor is failing to communicate properly, it should be replaced. Sensors may be returned to FT Technologies for further analysis if required (see Section 4.3).

Warning – The sensor contains no user serviceable components. Do not attempt disassembly as damage may result and product warranties will be invalidated.

During extreme weather conditions there may be periods where data is temporarily unavailable. However there are ways to mitigate against these affects. The following steps should be taken to ensure the highest levels of data availability from the sensor:

- Check that the wind sensor data and status flag errors are being processed as per the advice in Sections 6.4.29 and 6.4.30.
- Ensure that any installed surge and EMI protection (see Section 3) is in good condition and any cable shielding is terminated at both ends. All mating surfaces must be free of paint and corrosion.
- Check that the measurement cavity is in a satisfactory condition and no debris is present. Debris can be blown out or washed out with distilled water spray. Do not use mechanical tools to remove debris

Please contact FT Technologies for further information and advice if required.

4.3 Returns

If a sensor appears to be faulty, compile a detailed fault description for each sensor, then contact FT Technologies to request a Returns Materials Authorisation (RMA) form. Please complete the form and return as instructed. Returns cannot be accepted without prior approval via this authorisation form.

Units damaged by lightning or disassembled by the customer cannot typically be repaired, however an inspection fee may still apply.

4.4 Acu-Test Evaluation Kit

FT can provide Acu-Test Evaluation Kits and power supplies to assist users with connection, development and test of the FT sensors. The kit connects the sensor to a power supply and a Windows PC using virtual COM ports. The USB test cable converts RS485HD to USB.

The models described in this user manual use the FT050 Acu-Test cable:

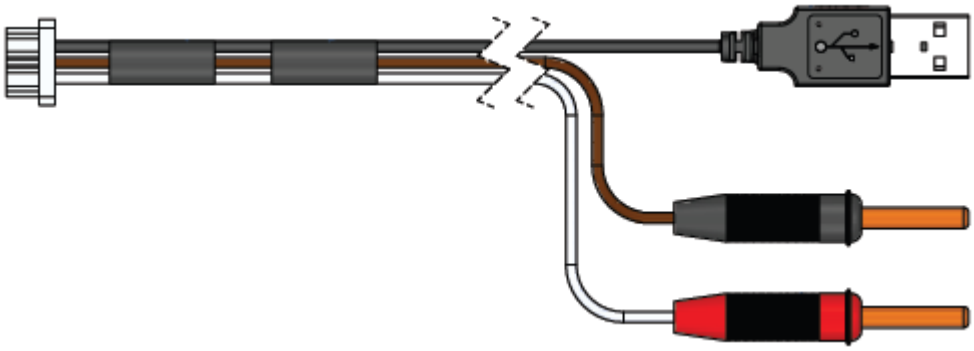


Figure 10: FT050 Acu-Test Evaluation Cable

The Acu-Test Evaluation Kit includes a USB test cable and a CD containing the Acu-Vis software installation files and user manuals. An external power supply capable of 6-30VDC and 0.1A is necessary, the FT062 power supply may be used in locations unsuitable for a benchtop electronics power supply.

Note: The FT062 power supply requires a regional C13-style adaptor for mains connection. See Figure 11.

Figure 11: The FT062 Power Supply (left) & Benchtop Electronic PSU Example (right)

The Acu-Test kit allows the user to view and modify configuration settings. The Acu-Test cable is not intended for long-term datalogging use.

Acu-Vis 2.0 software will work on a PC running Microsoft Windows 7, 8, 8.1 and 10.

Note: RS485 half-duplex sensors running in Continuous Update (CU) mode can be difficult to communicate with due to the limitations of half-duplex topology. Contact FT Technologies for assistance or disable CU mode using Acu-Vis 2.0

Caution: Live connection/disconnection of the power and/or sensors during live operation, or miswiring of the power leads could damage the equipment and is not covered by FT's standard warranty terms

Warning: Modifying settings may alter the performance of FT wind sensors, ensure the user understands the potential risks

Warning: Users should perform a risk assessment and be suitably trained before attempting to use any electrical equipment. Personal injury may result from unsuitable working practices

4.4.1 Software Installation

1. Insert the Acu-Vis 2.0 CD into the PC. Begin the installation by running the setup.exe file, it may be necessary to contact an IT administrator. Follow the on-screen instructions.

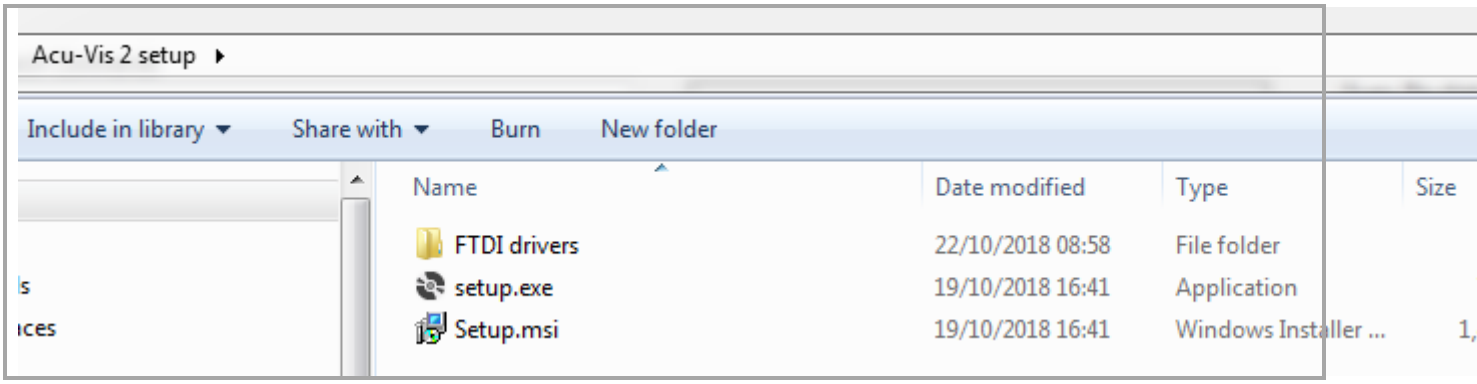


Figure 12: Acu-Vis Install Files

2. Remove the FT205 sensor and USB test cable from their packaging

3. Ensure the power supply is disabled

4. Connect the test cable to the relevant parts: Connect the +24VDC terminal of the power supply to the white wire (red test plug) and 0V terminal to the brown wire (black test plug). Connect the USB to a spare USB PC socket and remove any unnecessary USB devices

Figure 13: Acu-Test Cable Power Connections

5. Windows will automatically detect the USB cable and attempt to update the FTDI drivers

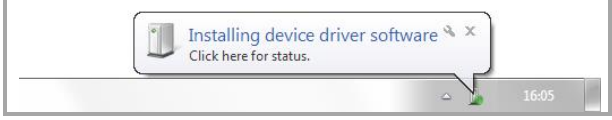
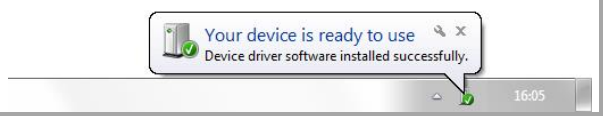
Please wait for Windows to install the hardware	Ready for use
	

Figure 14: Windows driver installation sequence

6. When the user is ready to operate the sensor - enable the power. When using a benchtop PSU ensure the required voltage is supplied (6-30VDC) and the current output is enabled

7. Once the above sequence is complete, wait approximately 5 seconds and then run Acu-Vis 2.0 by selecting the shortcut icon on the desktop or from the start menu in the FT Technologies folder.

Figure 15: Acu-Vis Windows Launch Icon

8. If you need to change the Acu-Test cable it is recommended to press the 'Disconnect' button and follow the exit process, close the Acu-Vis program and then disable the power. Remove the USB cable and replace with the required cable

In case of technical issues please contact the technical support team at FT Technologies.

4.4.2 Acu-Vis 2.0 Software Operation

Acu-Vis 2.0 opens on the Connect display window - press the green 'CONNECT' button to begin a user session, the program will detect the wind sensor if it is powered up and operating normally. If the sensor is in Continuous Update mode Acu-Vis 2.0 will disable it (and provide an option at the end of the session to re-enable it).

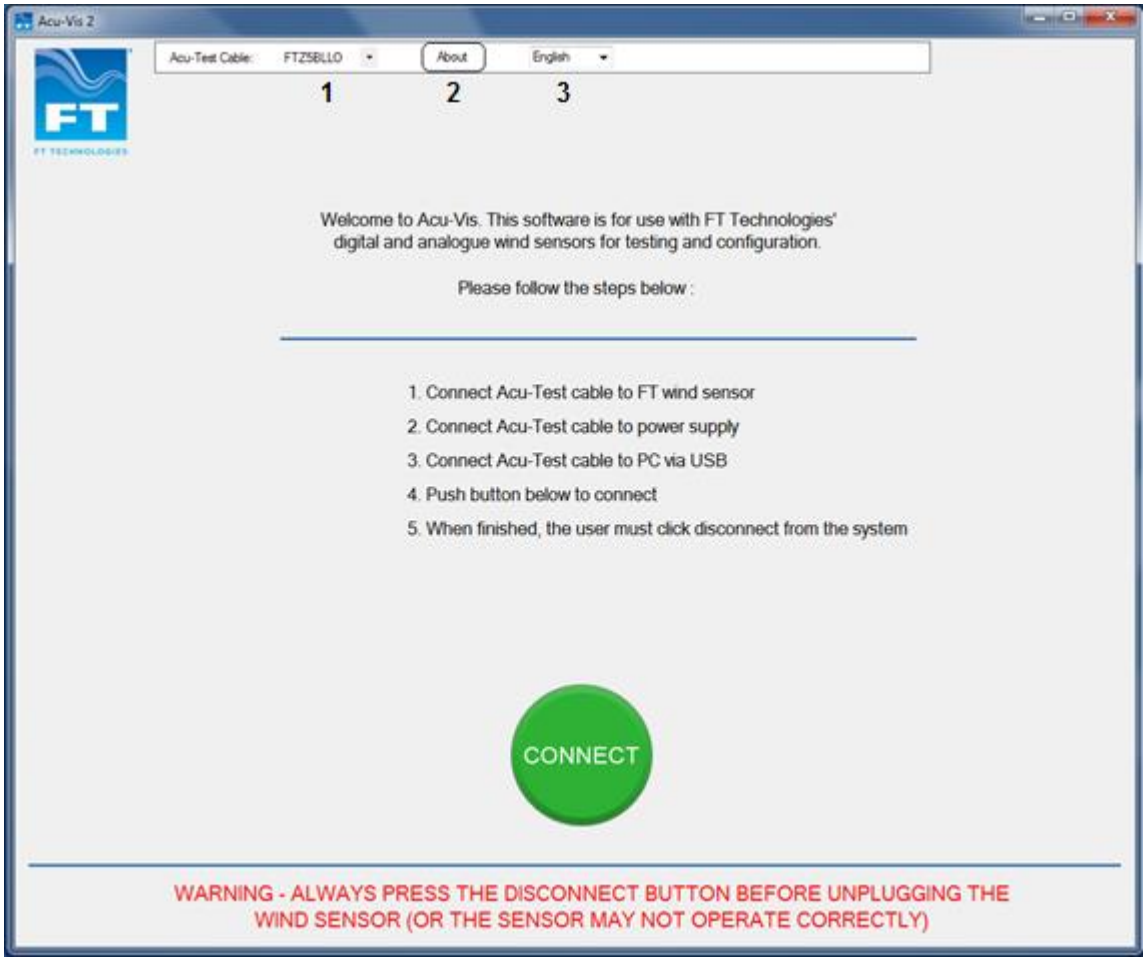


Figure 16: The Acu-Vis Home Screen

1. The Acu-Test cable serial number
2. About Window: FT Technologies contact information and software build versions
3. Language selection options: English, French, Chinese, Spanish, Japanese and Korean

Wind Readings Tab

The Wind Readings display includes sensor settings, real-time wind speed and direction data.

The temperature gauge on the right-hand side shows the Internal Temperature and the ‘Acoustic Temperature’ ambient air reading.

Note: Acoustic Temperature data requires software V7.5+ and an FT temperature calibration

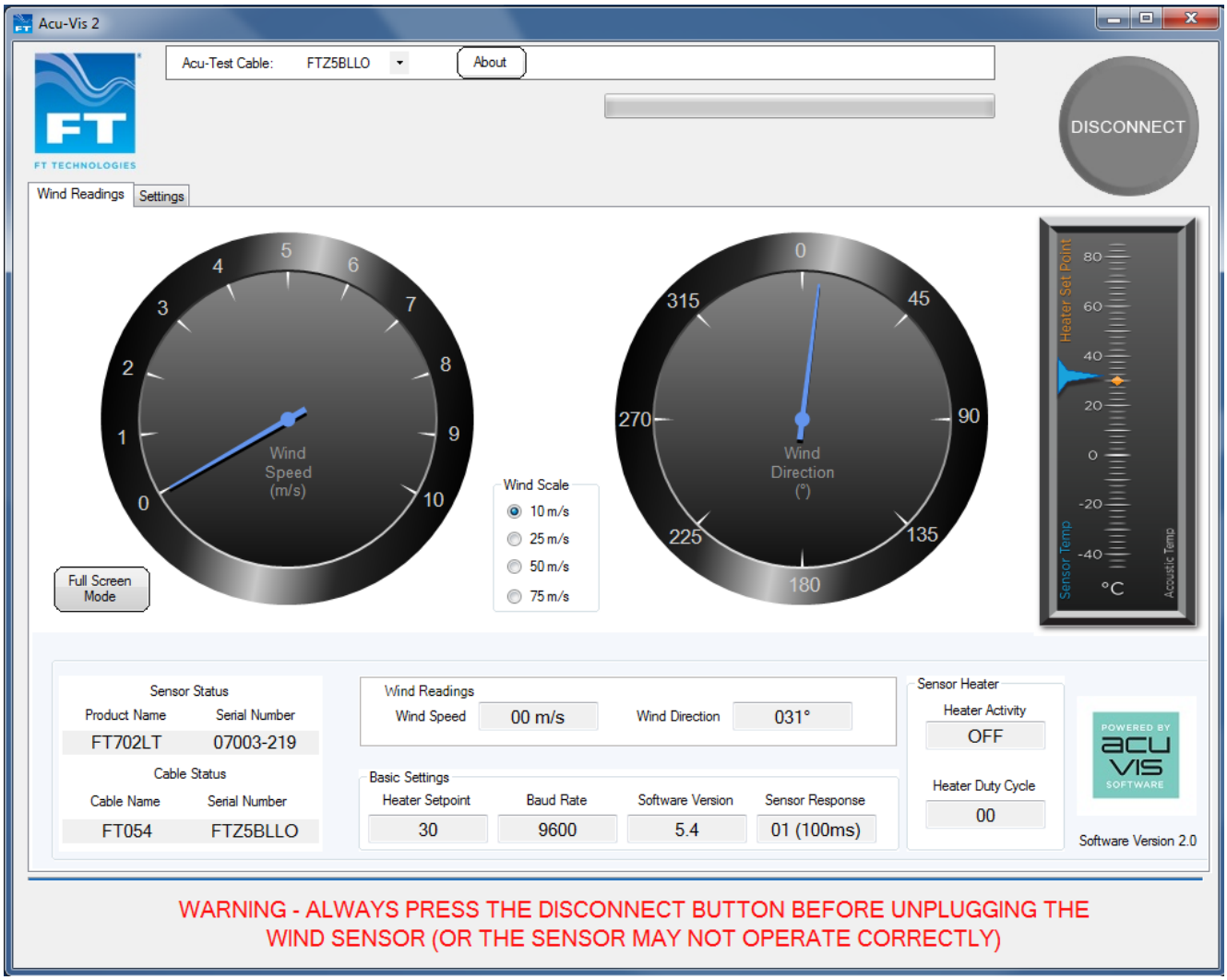


Figure 17: Acu-Vis 2.0 Live Display

Settings Tab

The Settings tab provides an interactive user interface for changing basic sensor settings with point and click operation. Consult the user manual for full software command details.

- Wind Speed & Direction Filter: On/Off and the averaging time period
- Wind Direction Datum Offset: Apply a directional offset to the sensor

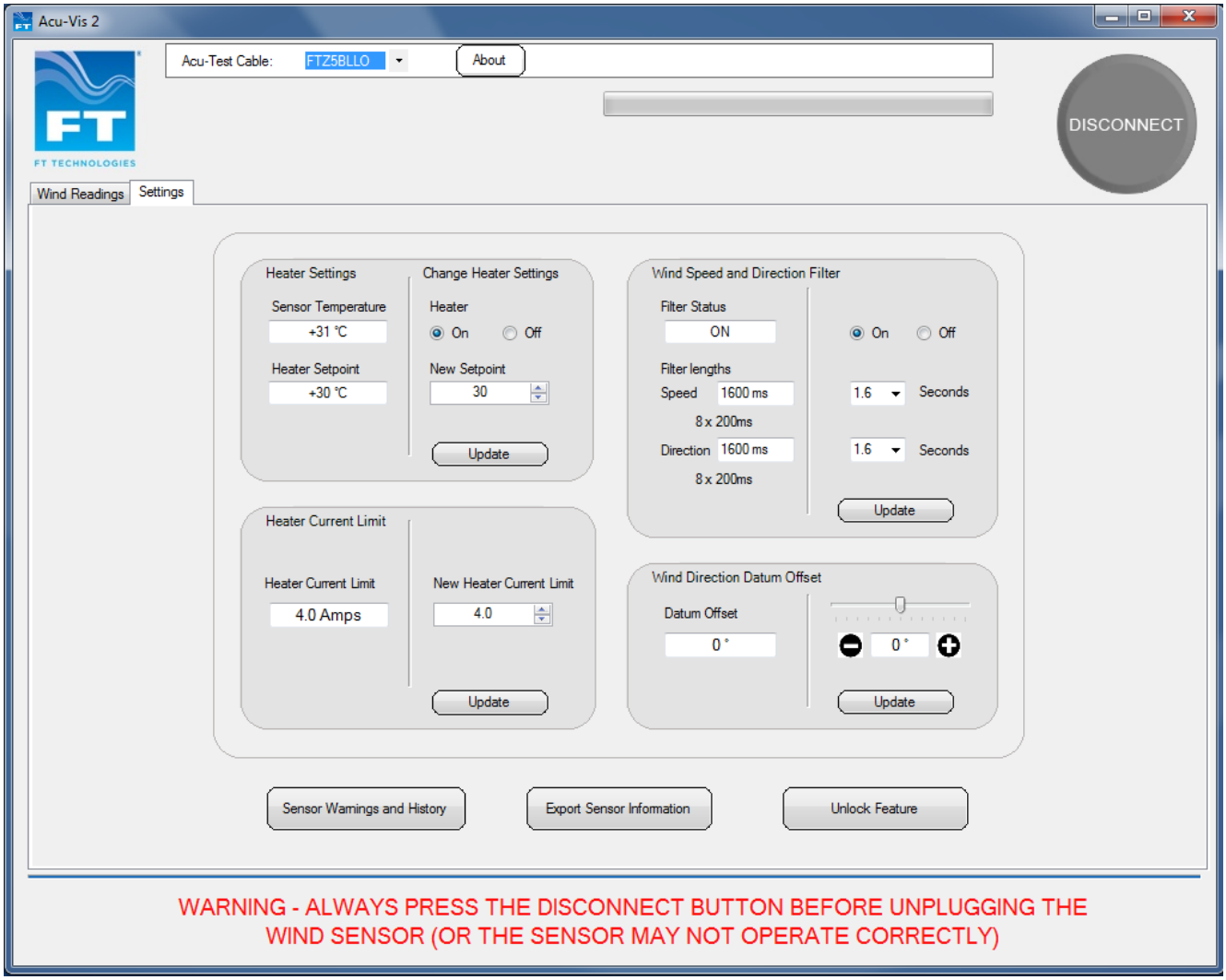


Figure 18: Acu-Vis 2.0 Settings Display

- The ‘Sensor Warnings and History’ button will provide a history of the connected sensor settings where it has been connected to the PC

- The ‘Export Sensor Information’ button creates an encrypted file containing current user settings and diagnostic information. This feature will export a file in .fff format that can be forwarded to the FT Technologies support teams

- The ‘Unlock Feature’ button is used to unlock advanced features in Acu-Vis 2.0, including the ‘Commands’ and the ‘User Calibration Table’ tabs. Contact FT Technologies for further details

Commands Tab

The Command tab allows the user to view and send various software commands:

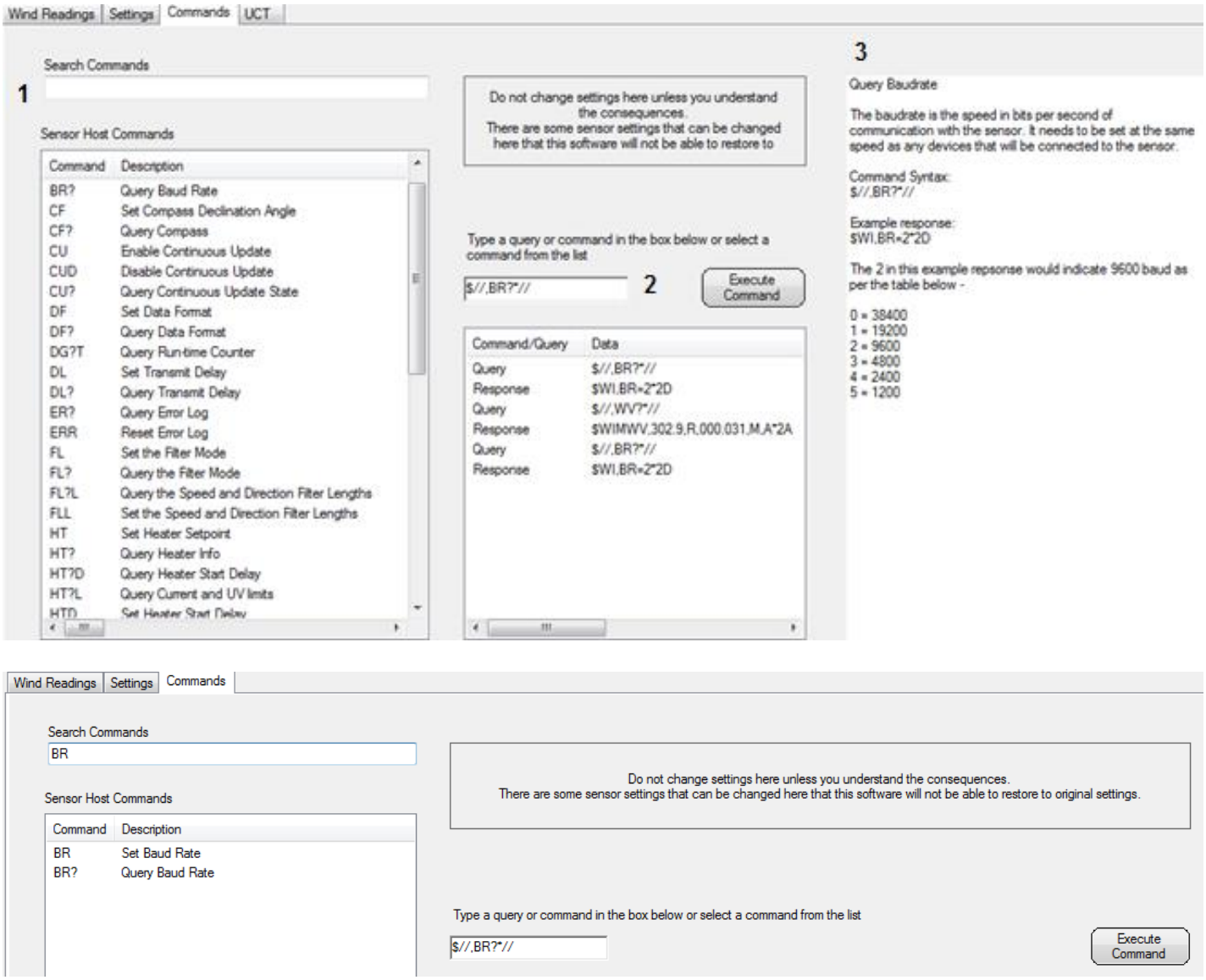


Figure 19: Command Line Terminal Display

- Search for commands (for example: BR) or select them from the 'Sensor Host Command' menu. Selecting a query will add the command to the 'Execute Command' window, a technical description will be displayed

- This window shows the command structure and allows the user to transmit commands using the 'Execute Command' button. If the command has a response it will be shown below

  Some SET commands require the user to add values into the command (for example: $//,DFP*//). The user will be prompted to enter the missing settings

  Note: The command console hides the <cr><lf> end-of-line terminal message and uses a default sensor ID of $// to communicate with all sensor ID numbers (// is a wildcard value)

- This window provides a description of the selected software command. Please refer to the user manual software command section for full descriptions

UCT ('User Calibration Table') Tab

The UCT window provides the user with a simple method of changing the calibration performance of the sensor. Refer to the UCT commands detailed in the user manual for further information.

Acu-Vis 2.0 will download any existing UCT settings and display them on the table and graph.

The easiest method of changing the UCT is to use the 'Standard % Offset" buttons to establish a calibration change.

When the calibration change has been selected press the orange 'Save UCT to Sensor' button and ensure the 'UCT Status' is set to Enabled.

Caution: This feature will change the calibration profile of the sensor and may compromise survey data and/or system performance

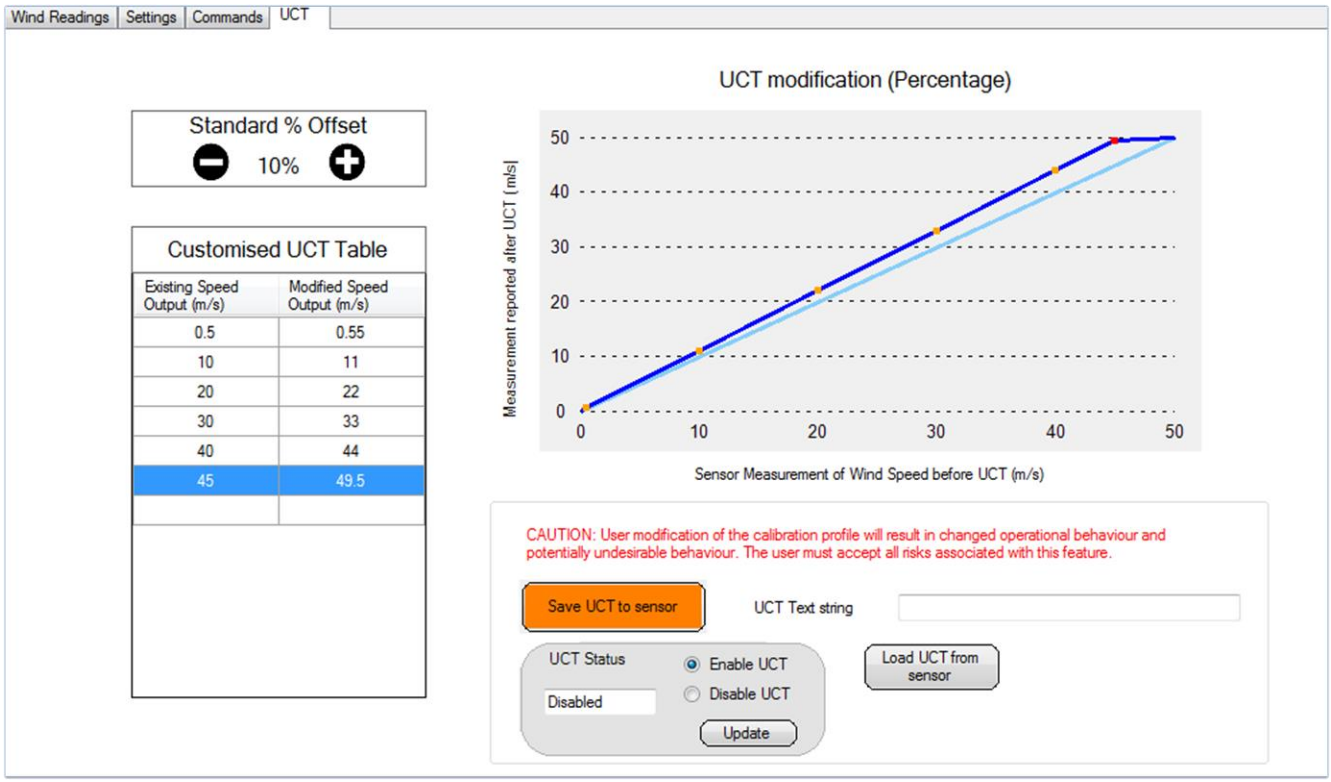


Figure 20: UCT Modification Window

4.4.3 Command Line Terminal Programs (Including Tera Term)

The FT050 Acu-Test cable can also be used to communicate via command line terminal programs, including Hyperterminal and Tera Term. This provides the user with a visible method of communication with digital wind sensors without building an RS485HD network.

To begin a Tera Term connection click 'New Connection…' in the File Menu:

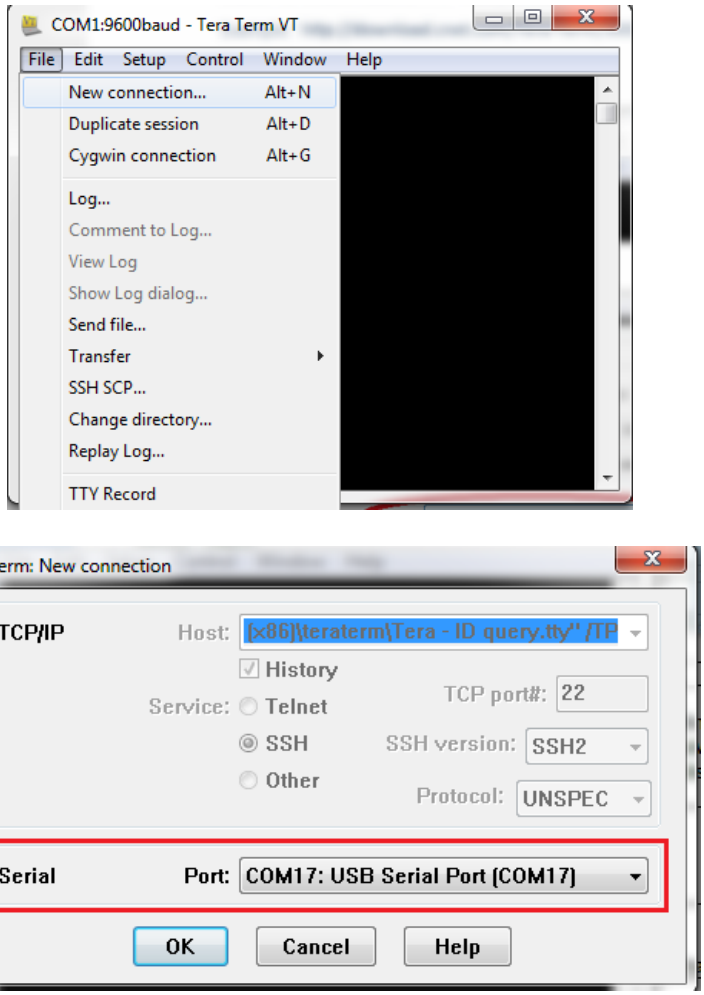


Figure 21: Creating a Connection in Tera Term

Create a new Serial connection, the COMx channel will be dynamically assigned by the user's computer, but should typically be recognised as a 'USB Serial Port'.

It is necessary to modify several settings to view the data and simplify the end-of-line character requirements of software commands (i.e. remove the requirement to type <cr><lf> at the end of all commands).

- Navigate to the 'Terminal Setup' window from the top menu: Setup > Terminal
    a. Set the 'New-Line Transmit' setting to: "CR+LF"
    b. Enable 'Local Echo' by ticking the box (Local Echo makes typed characters visible on the display)

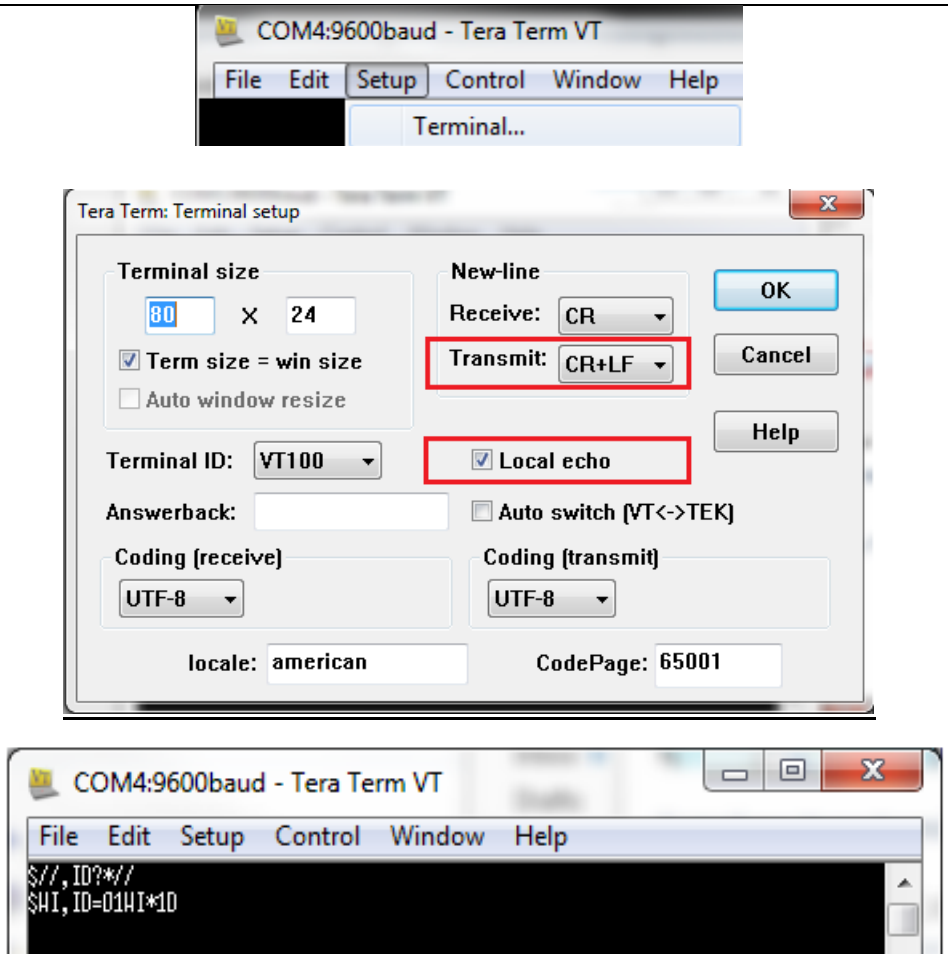


Figure 22: Modifying Terminal Settings in Tera Term

Tera Term defaults to a baud rate of 9600, it may be necessary to configure this setting via the Setup menu → Serial Port… settings window.

With connection enabled with the settings configured as described above, send commands to the sensor to confirm successful connection. Please note that in half-duplex communication protocols the sensor cannot receive commands while simultaneously transmitting information, therefore it may be necessary to repeat the command and confirm it was accepted using a QUERY command. This can be an issue when using CU mode at high frequencies.

Below are some useful commands:

$01,ID?*//	Query the sensor ID setting
$01,CU?*//	Query the CU mode setting
$01,CUD*//	Disable CU mode
$01,CUE00010*//	Enable CU mode at 1 second intervals (1Hz). Note: Command is for FT205 sensors only.

The // line bypasses the checksum validation. Checksum validation is recommended for production datalogging to improve data integrity. See Section 5 and 6 for further details regarding command structures and replies.

Note: If a sensor is set to an ID setting other than 01, replace $01 with the alternative ID. Starting a command with $// will perform the relevant command on all connected sensors.

5 SENSOR COMMUNICATION

5.1 Introduction

The sensor features an easy to use ASCII-based communication protocol transmitted over either RS422 (full-duplex), RS485 (half-duplex) serial link or buffered UART (full-duplex, 3V and 5V TTL compatible). The protocol incorporates checksum validation to ensure the integrity of all data transmissions. In addition to the FT Technologies proprietary protocol the sensor can output the common NMEA 0183 MWV (Wind Speed and Angle) sentence. Refer to Section 6.4.7 for information on how change communication mode.

The different communication protocols require consideration by a suitably experienced engineer for the required functionality. Below are some generalised (but not comprehensive) points:

- RS422 networks permit multiple FT wind sensors to be connected. The 4-wire connection allows full-duplex operation but may use more current in certain configurations
- RS485 (half-duplex) networks permits multiple FT wind sensors to be connected. The 2-wire connection permits half-duplex operation and may require additional software controls when multiple wind sensors are connected to a network. 2-wire networks may be simpler to build
- UART networks permit 1 FT sensor to be connected in a 2-wire connection. Typically used with shorter cable lengths

The user should review the compatibility of their intended application with the proposed communication standard. User applications may require specific wiring, timing, control logic and safety processes.

5.2 RS422 & RS485 Protocol

Slew-rate limited drivers are used to reduce EMI and minimize reflections from improperly terminated transmission lines and stubs. The signal state definitions for the serial interface data lines are as follows:

- RS485 The idle, marking, logical “1”, OFF or stop bit state is defined by a negative voltage on line A with respect to line B.
- RS485 The active, spacing, logical “0”, ON or start bit state is defined by a positive voltage on line A with respect to line B.
- RS422 - The idle, marking, logical “1”, OFF or stop bit state is defined by a negative voltage on line A with respect to line B.
- RS422 - The active, spacing, logical “0”, ON or start bit state is defined by a positive voltage on line A with respect to line B.

Circuit examples are provided in Figure 23 and Figure 24. Refer to Section 6.4.7 for information on how change communication mode.

If two or more wind sensors are to be installed, it is possible to use the same 2-wire RS485 data link to connect all the sensor units to the computer.

Before using a RS485 configured sensor in a multi-device system, the Listener identifier of each sensor must be set to a unique value. Use the ID command (Section 6.4.17) to set the Listener identifier for each sensor. If the Listener identifiers are being set in the final host system, then it is important that only one sensor be connected at a time to the RS485 bus until all devices have been assigned a unique Listener ID. Great care should be exercised when using the ‘//’ characters for addressing. The ‘//’ address characters can be used to send a SET command simultaneously to all sensor units (for example, to enable or disable filtering). Under no circumstances should the ‘//’ characters be used with any QUERY commands since this will cause all sensor units to transmit data resulting in bus contention.

RS422 is a multi-drop communication standard that permits network topologies containing one transmitter and multiple receivers.

In RS422 configuration the default setting of the FT transmitter is to only enable while transmitting commands. A software command (see Section 6.4.7) exists to activate the transmitter permanently, typically resulting in additional current draw depending on network configuration. Termination and bias resistors generally improve data integrity but may not be necessary if short cable lengths (0-2m), low baud rates and when modern 'fail-safe' transceivers are used. The FT205EV uses 'fail-safe' transceivers. Removing the resistors may result in lower current draw.

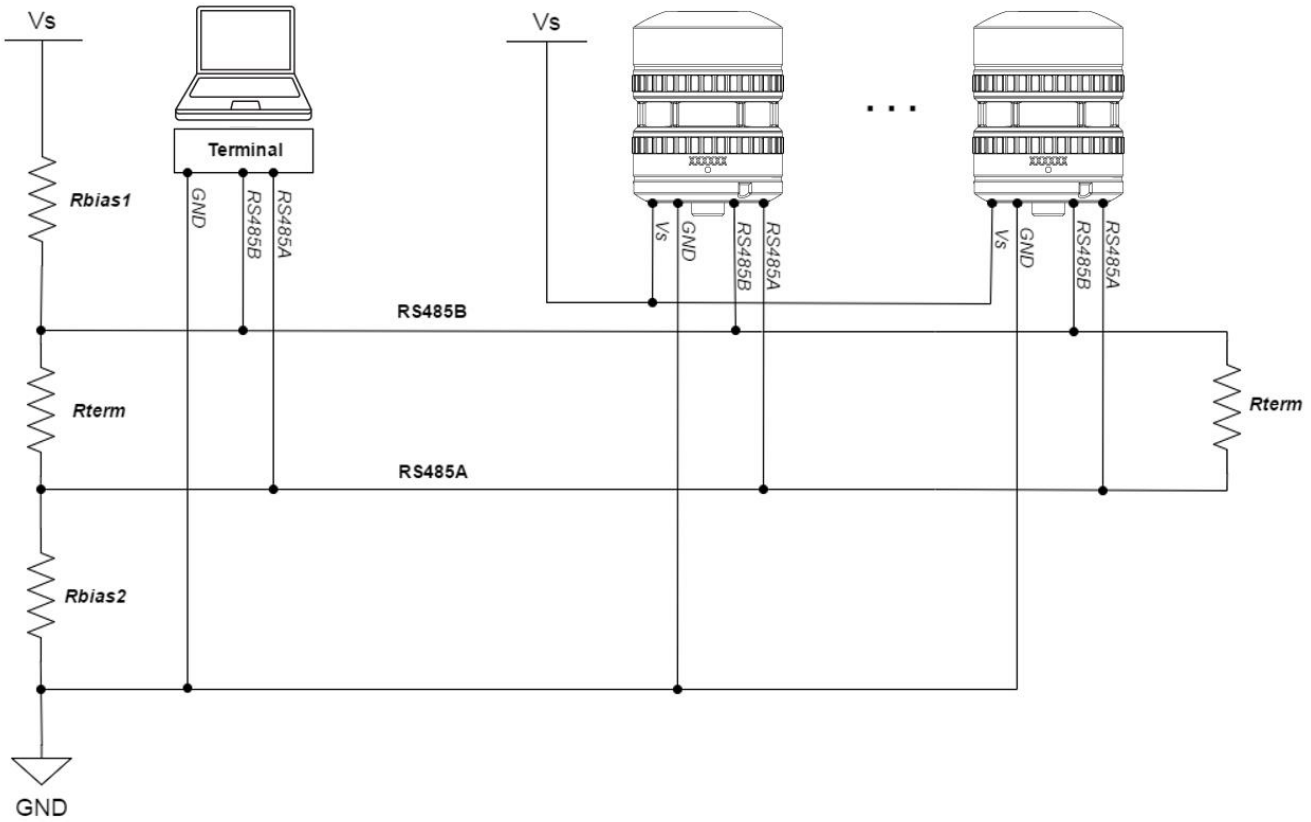


Figure 23: RS-485 Connection Diagram for 2 Wind Sensors

Notes:

1. Data lines A & B should be twisted-pair type (characteristic impedance 120Ω). The cable should incorporate overall screening braid which should be connected to the chassis at each circuit node.
2. Surge protection is not shown.
3. Subject to testing, the bias resistors may be omitted, if the terminals RS485 converter makes use of a fail-safe RS485 transceiver.
4. Subject to testing, one or both termination resistors may be omitted only if biasing is **not** needed and the transceivers are slew-rate limited.
5. Resistors should be of the anti-surge variety and rated at 1W or greater, such as the Tyco CCR range. Rbias2 = 750Ω, Rterm = 120Ω, see table below for Rbias1 values at various voltages (E24 series). If operating at a voltage other than what is specified in the table, select Rbias1 based on the equation below. Round the resistor value up rather than down when selecting from the E24 range.

$$Rbias1\ (Vs) = \frac{Vs \times 754}{3.125} - 754$$

Supply Voltage (V)	Rbias1 (Ω, E24 5%)
6	715
12	2200
24	5100
30	6800

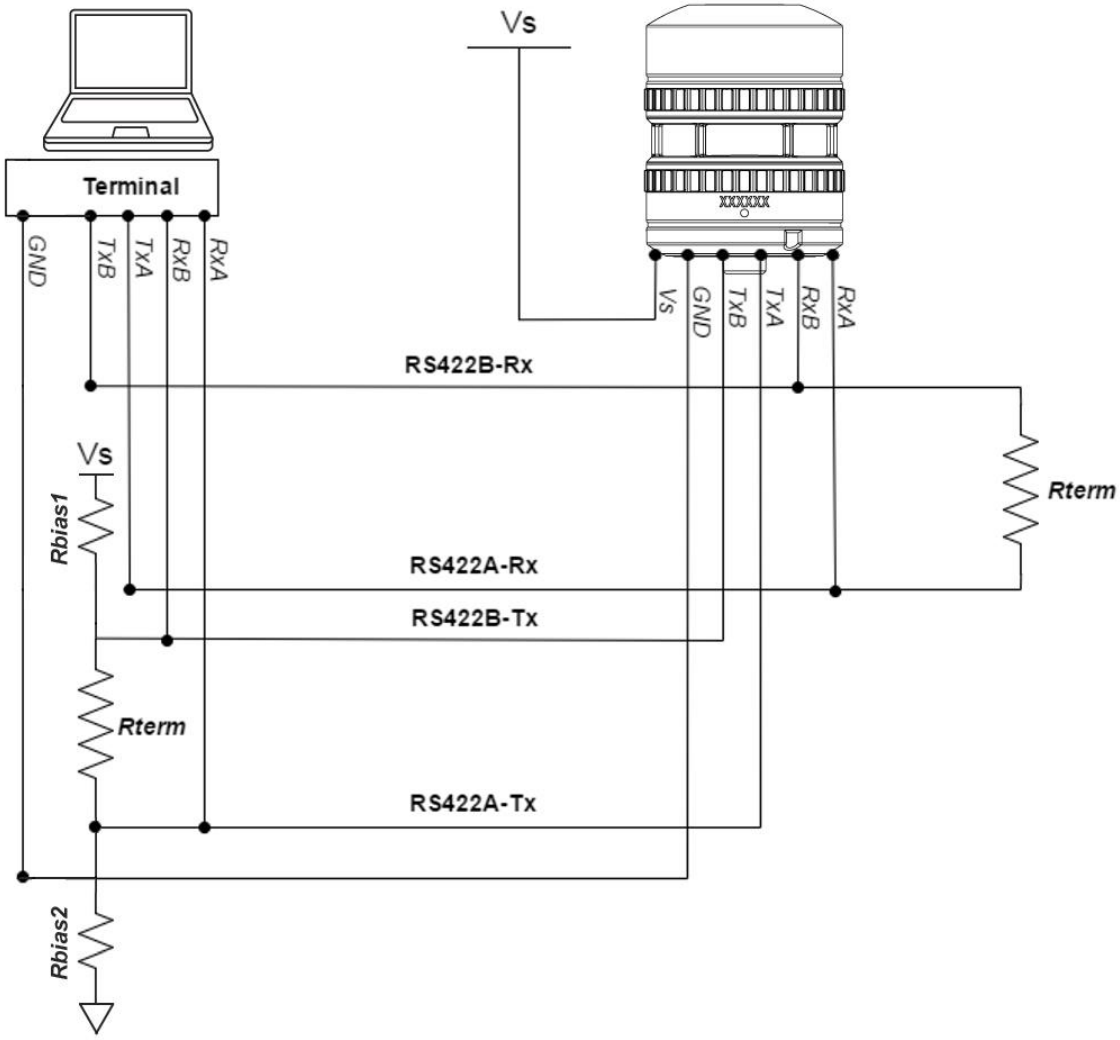


Figure 24: RS-422 Connection Diagram

Notes:

1. Data lines A & B should be twisted-pair type (characteristic impedance 120Ω). The cable should incorporate overall screening braid which should be connected to chassis at each circuit node.
2. Surge protection is not shown.
3. Subject to testing, the bias resistors may be omitted, if the terminals RS422 converter makes use of a fail-safe RS422 transceiver.
4. Subject to testing, one or both termination resistors may be omitted only if biasing is **not** needed and the transceivers are slew-rate limited.
5. Resistors should be of the anti-surge variety and rated at 1W or greater, such as the Tyco CCR range. Rbias2 = 750Ω, Rterm = 120Ω, see table below for Rbias1 values at various voltages (E24 series). If operating at a voltage other than what is specified in the table, select Rbias1 based on equation below. Round the resistor up rather than down when selecting from the E24 range.

$$Rbias1\ (Vs) = \frac{Vs \times 754}{3.125} - 754$$

Supply voltage (V)	Rbias1 (Ω, E24 5%)
6	715
12	2200
24	5100
30	6800

5.3 UART Protocol

UART is typically used over short transmission distances (typically 0-600mm) and can only support one master (controller) and 1 slave (wind sensor) device.

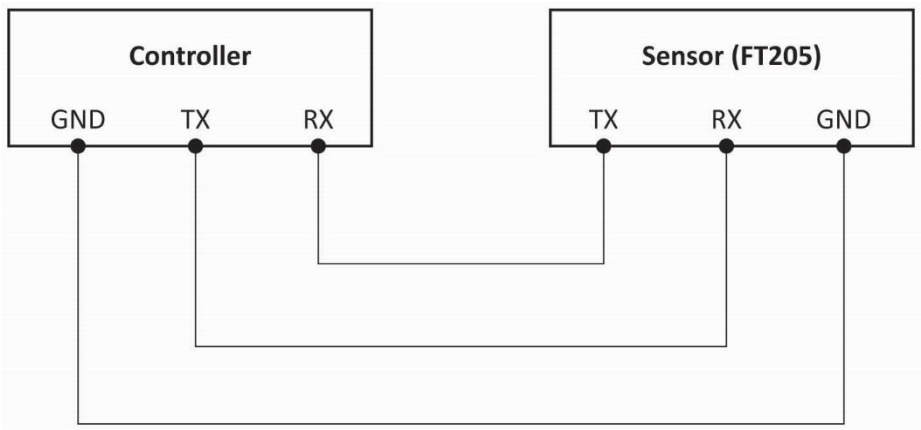


Figure 25: UART Connection Diagram

Notes:

1. 3/5V TTL compatible

5.4 Configuring the Sensor

All user parameter settings are stored in non-volatile memory and are retained when the sensor is switched off. When the sensor is next switched on (or a user reset command is sent) the sensor will revert to these settings. The sensor can therefore be configured prior to final installation if required.

The sensor settings can be returned to the factory values (see Figure 30 for factory default settings) at any time by sending the factory reset command.

5.5 Communication

5.5.1 Conventions used in this manual

All examples of sensor transmitted and received messages are printed in italic courier monospace font, e.g.

$<listenerID>,DFP<checksum><cr><lf>*

Angle brackets are used as placeholders for data (e.g. <wind speed>) or for non-printable ASCII characters (e.g. <cr> for carriage return).

Figure 26 lists the various special characters and symbols which are used in the examples given in this Handbook.

Symbol	Valid Characters	HEX Values	Definition
a	{A to Z} {0 to 9} {/}	41-5A, 30-39, 2F	Talker/listener address field characters
c	{A to Z} {0 to 9}	41-5A, 30-39	Fixed length field of alpha (upper case only) and numeric characters
h	{A to F} {0 to 9} {/}	30-39, 41-46, 2F	Checksum field validation characters
s	{ }	20	Space
x	0 to 9	30-39	Fixed length field of numeric characters
x.x	{0 to 9} {.}	30-39, 2E	Fixed point numeric field (i.e. always with leading and trailing zeros)
±	{+ -}	2B, 2D	Polarity indicator. Where a value can take on both positive and negative values a polarity indicator (either + or -) is always sent as the first character in the field. The field length therefore remains fixed for both positive and negative values.
	{$}	24	Start of message delimiter
	{*}	2A	Checksum field delimiter
	{,}	2C	Field delimiter
-	{-}	2D	Dash
<cr>		0D	Carriage return / Line feed — End of message delimiter
<lf>		0A	
<name>			Placeholder for data

Figure 26: Symbols used in this Handbook

5.5.2 Data Transmission

Data is transmitted and received via an asynchronous serial communication interface using ASCII characters. The interface operates with the following parameters:

Parameter	Setting
Baud Rate	1200, 2400, 4800, 9600 (factory default), 19200, 38400
Data Bits	8
Start Bits	1
Stop Bits	1
Parity	None

Figure 27: Data Transmission Parameters

To set the sensor baud rate use the BR command (Section 6.4.5).

The sensor does not use handshaking (either hardware or software) to control the flow of data to and from the host computer. It is important, therefore, that the serial interface of the host computer is set with handshaking/flow control disabled.

5.5.3 Message Format

Data communication between the sensor and the host computer is performed by the transmission of ASCII messages. Figure 28 shows the composition of the message. The same message format is used for both received and transmitted messages.

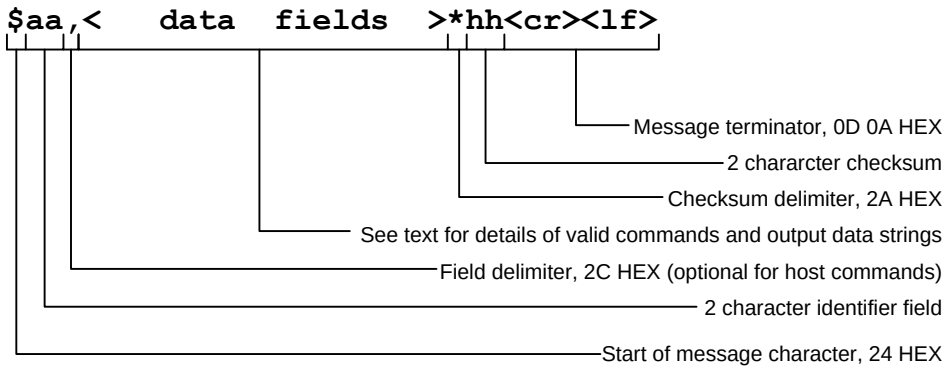


Figure 28: Message Format

All messages start with the '$' start of message character, followed by the 2 character talker/listener identifier (see Section 5.5.4) field.

Following the first delimiter is the main body of the message which comprises a variable number of data fields (dependent on the message being transmitted), each separated by the field delimiter character (','). Data fields may contain alpha, numeric, or alphanumeric data depending on the information content of the field.

Messages sent to the sensor will contain a command in <data fields> and messages transmitted from the sensor will contain output data in <data fields>.

The data field section of the message is terminated by the checksum delimiter character '*'. Following the checksum delimiter is the two-character checksum field. See Section 5.5.5 for information on how to compute the checksum and Section 5.5.6 if checksum message validation is not required.

All messages are terminated with a carriage return <cr> and line feed <lf>.

5.5.4 Listener and Talker Identifiers

The sensor is assigned with both a Listener and Talker identifier address that allows an individual sensor to be uniquely identified in a system comprising more than one sensor.

Whenever a message is sent to the sensor, the identifier field of the message (the 2 characters immediately following the '$' start of message character) must correspond to the sensor Listener identifier address, otherwise the sensor will ignore the message. In applications where more than one sensor is connected to the communication bus, you should assign each sensor in the system a unique Listener ID. The host computer will then be able to address individually each sensor. If you do not wish to use the Listener ID in messages sent from the host computer, you can replace the Listener ID with '//'. Sending '//' in place of the Listener ID will allow any sensor, irrespective of its Listener ID setting, to respond to the message.

Whenever a message is transmitted from the sensor, the identifier field of the message (the 2 characters immediately following the '$' start of message character) will contain the Talker ID. The Talker ID is used as a message tag to identify which sensor has transmitted the message.

The factory default value for the Listener ID is 01 and for the Talker ID it is WI (Weather Instrument). To change the Listener and/or Talker ID use the ID Command (Section 6.4.17).

5.5.5 Calculating the Message Checksum

All messages sent to, or received from, the sensor include a checksum field. Messages that are transmitted from the sensor always include a checksum value in the checksum field. Messages sent to the sensor by the host computer can either contain a checksum value or an 'ignore checksum identifier' in the checksum field.

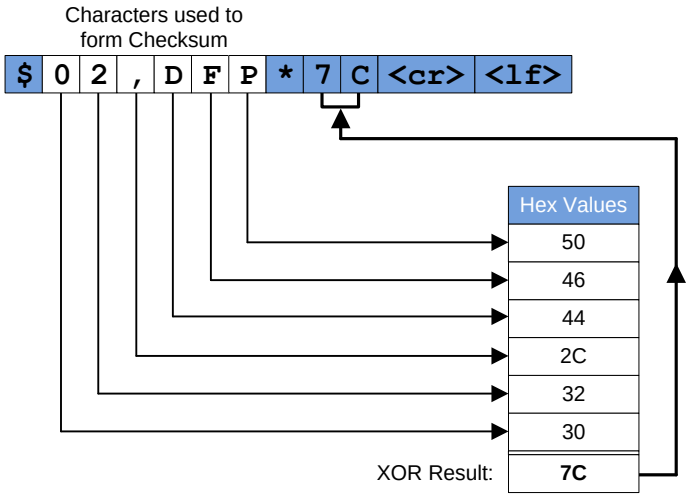


Figure 29: Checksum Example

The checksum value is calculated by Exclusive OR'ing (XOR'ing) all the bytes between (but not including) the '$' and the '*' characters of the message. The resulting single byte value is then represented by 2 HEX characters in the message string. The most significant character is transmitted first.

Note: Since a message only contains ASCII characters (which have values in the range 0-7F) the checksum value will always be between 0 and 7F.

5.5.6 Disabling the Checksum

All messages which are sent to the sensor must contain a valid checksum value in the checksum field, otherwise the sensor will not process the incoming message. Although it is recommended that a checksum value be computed for all messages which are sent to the sensor, in some cases this may not be convenient (i.e. when communicating with the sensor with a terminal). To prevent the sensor from performing checksum validation of incoming messages, send the ASCII characters '//' in place of the checksum value.

Example:

Send a message to set the data output format to Polar using the DFP command (the sensor Listener ID in this example is set to 02)

With a checksum (sensor checksum validation automatically enabled):

*$02DFP*50<cr><lf>*

Without a checksum (sensor checksum validation automatically disabled):

$02DFP//<cr><lf>*

A checksum value is always transmitted by the sensor with every outgoing message. However the checksum field can be ignored by the host computer if checksum validation for received messages is not required.

6 PARAMETER SETTINGS

6.1 Command Types

6.1.1 Set Commands

Figure 30 lists the commands that may be sent to the FT205EV sensor from the host computer that are used to SET configuration options for the wind sensor.

Command	Mnemonic	Configuration Options	Factory Default	Section
Anemometer Mount	AM	Normal Inverted	Normal	6.4.1
Acoustic Temperature Units	AT	C (Celsius) F (Fahrenheit) K (Kelvin) Filter Length	C (Celsius) 1 minute	6.4.3 6.4.4
Serial interface baud rate	BR	1200, 2400, 4800, 9600, 19200, 38400	9600	6.4.5
Compass Settings	CF	Enabled or disabled 000.0° to 359.9° Declination angle	Disabled 0.000°	6.4.6
Communication Interface	CI	RS485 RS422 (always enabled) RS422 (enabled during tx) UART	RS485	6.4.7
Continuous Update	CU	Enable or Disable Update interval, 0.1-6000 seconds	Disabled	6.4.8
Wind velocity data format	DF	Polar, NMEA 0183, Combined	Polar	6.4.9
Command delay interval	DL	00 to 20	01	6.4.11
Clear Error Report	ER	Reset	000000000000	6.4.12
Wind velocity filter	FL	Enabled or Disabled Speed filter length Direction filter length	Enabled 0016 0016	6.4.13 6.4.14
Selective Filter	FL	Enable or Disable Selective filter length	Disabled 010	6.4.15
Heater settings	HT	No heating functionality is provided on the FT205 platform.		6.4.16
Listener and talker identifiers	ID	Listener ID = xx Talker ID = xx	Listener ID = 01 Talker ID = WI	6.4.17
Min/Max wind speed	MM	Reset	999.9,000.0	6.4.18
Overspeed Warning Scheme	OS	Enabled or disabled	Disabled	6.4.19
Reset	RS	Load Current Settings, Load Saved Parameters	NA	6.4.20
User Calibration Table	UC	Enable or Disable Clear Wind speed table record Save wind speed table Table label	Disabled NA NA NA	6.4.23 6.4.24 6.4.25 6.4.26 6.4.27
Save User Parameters	US	Copies current Parameters	NA	6.4.28

Figure 30: Set Commands

When a valid message is recognised by the sensor, the sensor will carry out the command contained in the message. To verify that the command has been successfully carried out, an associated QUERY command can be sent after most SET commands (see Section 6.1.2 for the list of parameters which may be queried).

6.1.2 Query Commands

Figure 31 lists the commands that may be sent to the sensor from the host computer that are used to QUERY the wind sensor's latest readings or configuration.

Command	Mnemonic	Sensor Data Returned	Section
Anemometer Mount	AM	Normal Inverted	6.4.1
Acoustic Temperature	AT	Temperature Temperature Units (°C, °F, K) Filter time period	6.4.2 6.4.3 6.4.4
Serial interface baud rate	BR	1200, 2400, 4800, 9600, 19200, 38400	6.4.5
Compass Settings	CF	Enabled or Disabled Compass status 000.0° to 359.9°	6.4.6
Communication Interface	CI	RS485 RS422 (always enabled) RS422 (enabled during tx) UART	6.4.7
Continuous update	CU	Enabled or Disabled Update interval (0.1 - 6000 seconds)	6.4.8
Wind velocity data format	DF	Polar, NMEA 0183 or Combined	6.4.9
Runtime Counter	DG	Number of hours of runtime	6.4.10
Command delay interval	DL	00 to 20	6.4.11
Error report	ER	Factory Report	6.4.12
Wind velocity filter	FL	Enabled or Disabled Speed filter length, 1-64 Direction filter length, 1-64	6.4.13 6.4.14
Selective Filter	FL	Enabled or Disabled Validity Period	6.4.15
Heater settings	HT	No heater functionality is provided on the FT205 platform	6.4.16
Listener and talker identifiers	ID	Listener ID = xx Talker ID = xx	6.4.17
Min/Max wind speed	MM	Min and Max Speeds Recorded	6.4.18
Overspeed Warning Status	OS	Enabled or Disabled	6.4.19
Serial Number	SN	Serial Number	6.4.21
Software Version	SV	Software Version	6.4.22
User Calibration Table	UC	Enabled or Disabled Wind speed table record Table label	6.4.23 6.4.24 6.4.25 6.4.26 6.4.27
Saved User Parameters	US	Matches Saved to Current User Parameters	6.4.28
Wind velocity reading	WV	Wind Speed, Direction and Sensor Status (temperature optional)	6.4.29 6.4.30

Figure 31: Query Commands

6.2 User Calibration Table

The User Calibration Table includes up to 64 user programmable records. Each record comprises a pair of values representing the corrected speed (wind tunnel speed) and the corresponding uncorrected wind sensor speed. In addition to the calibration table, there is provision for a user-defined text string of up to 32 characters which is stored together with the table.

The User Calibration Table records must be entered in ascending order of wind sensor speed. The minimum allowable difference between wind sensor speed values in consecutive records is 0.5m/s.

To load the User Calibration Table with data, the following steps need to be taken:

1. The Table must first be cleared (See Section 6.4.24).
2. Each pair of table row values is entered into a RAM copy of the User Calibration Table (See Section 6.4.25)
3. A text string linked to the table may be entered if desired. This can be entered at any point after the table is cleared and before the RAM copy of the table is saved into Flash memory. (See section 6.4.27)
4. The RAM copy of the User Calibration Table is saved into Flash memory (See Section 6.4.26)

At any point in the above procedure (or at any other time) commands can be sent to the wind sensor to:

- Verify that the table has been cleared;
- Verify the last row of data written to the table;
- Read the number of table entries and the table checksum;
- Read out a selected row of table data,
- Read out the User Calibration Table label.

See Sections 6.4.23 - 6.4.27 for further details.

6.3 Timing Constraints

When a valid command is received by the sensor input buffer, there will be a time delay whist the command is being processed. The actual command latency depends on exactly when the last character of the command is received within the sensor internal processing cycle. The sensor can process only one SET or QUERY command at a time.

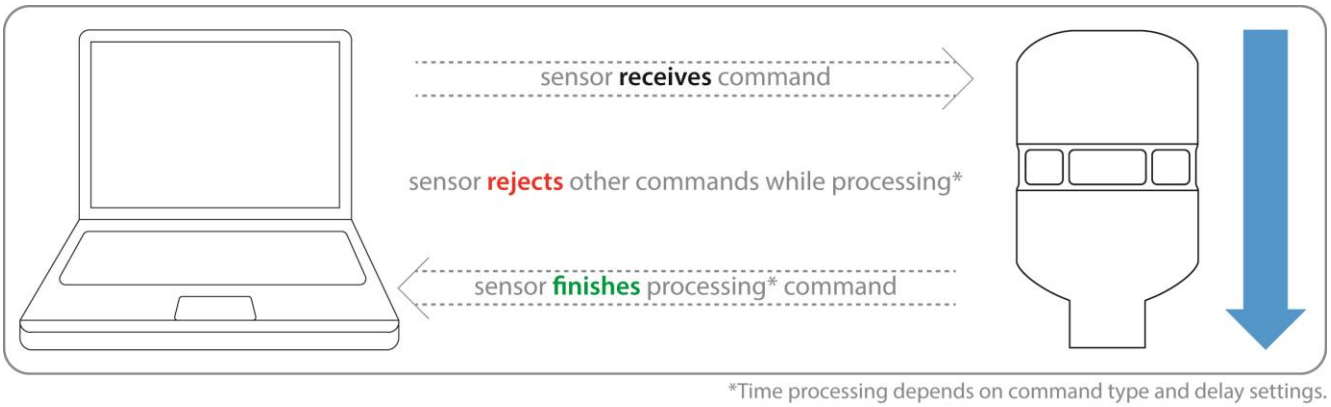


Figure 32: Command Processing

Once a SET command has been received by the sensor, it can take approximately 400ms for the command to be processed and any setting change implemented. If other commands are sent during this period, they may be ignored by the wind sensor. Therefore all SET commands must be separated by a period of at least 500ms before further commands are sent. (Or longer in the case of a Reset command being sent See Section 6.4.20).

Once a QUERY command has been received by the sensor, it takes up to 50ms for the command to be processed. The sensor will then wait for a predefined delay before sending a response. This delay time is programmable in increments of 50ms.

See Section 6.4.11 for details of how the delay between the sensor receiving a command and transmitting a reply can be adjusted. An additional latency is recommended depending on the time taken for the computer to switch between transmit and receive modes.

If the delay time has been extended using the DL command, then the next QUERY command sent to the wind sensor must be separated by the maximum QUERY command processing time (50ms) and at least the DL interval (50ms default.) It is therefore recommended that the frequency of any QUERY command does not exceed 10Hz, i.e. 10 commands per second.

Message Example:
For example, to set the wind velocity output to Polar format and verify that the command has been accepted, send the following commands:

Set the wind reading format to polar:

```
$//DFP*//<cr><lf>
```

Then wait 500ms for the SET command to be implemented by the sensor.

A QUERY can then be sent to confirm command has been carried out:

```
$//DF?*//<cr><lf>
```

Then wait 50-100ms for the sensor to send a response:

```
$WI,DF=P*5D<cr><lf>
```

Please note the above example assumes the sensor has a factory default time delay of 50-100ms (DL01).

6.4 Command Parameters

Each command, and its usage, is described in the following Sections. All examples, other than where stated, assume that the sensor Listener ID is set to 01, and the sensor TalkerID is set to WI, (Weather Instrument).

6.4.1 AM: Set or Query Anemometer Mount Orientation

Command Parameter	AM

Command Syntax		
	SET Sensor:	*$<listenerID>,AM<orientation>*<checksum><cr><lf>* *$aa,AMx*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,AM?*<checksum><cr><lf>* *$aa,AM?*hh<cr><lf>*
	Sensor output:	*$<talkerID>,AM=<orientation>*<checksum><cr><lf>* *$aa,AM=x*hh<cr><lf>*

Parameters	<orientation>	
	N	Set Normal orientation for mounting the sensor in 'regular' orientation
	I	Set Inverted orientation for mounting the sensor 'upside down'

Examples	Example 1 Set the anemometer mount orientation to inverted and verify the new setting:	
	Message	Comment
	$01,AMI//<cr><lf>*	Set Inverted orientation
	$01,AM?//<cr><lf>*	Query orientation setting
	*$WI,AM=I*4A<cr><lf>*	Inverted orientation setting

Description	Use the AM command if changing the mounting of the anemometer between right way up and upside down. In inverted orientation the sensor's compass and wind direction readings will be reversed to provide correct direction and heading output.

6.4.2 AT.1: Query the Acoustic Temperature

Command Parameter	AT

Command Syntax	SET Sensor:	*N/A*
	QUERY Sensor:	*$<listenerID>,AT?*<checksum><cr><lf>* *$aa,AT?*hh<cr><lf>*
	Sensor output:	*$<talkerID>,AT=<temp>,<units>,<status>*<checksum>* *<cr><lf>* *$aa,AT=±xxx.x,c,c*hh<cr><lf>*

Parameters	<temp>	
	-077.8 to +368.3	Read only parameter that returns the current acoustic temperature reading in the range: -61.0°C to +95.1°C -77.8°F to +203.2°F 212.2K to 368.3K
	<units>	
	C	The acoustic temperature is output in degrees Celsius
	F	The acoustic temperature is output.in degrees Fahrenheit
	K	The acoustic temperature is output in Kelvin
	<status>	
	V	The acoustic temperature reading is valid.
	A	An acoustic temperature reading is being acquired. The output may not be valid during this time.

Examples	Example 1 Query the latest acoustic temperature reading – a valid reading in degrees Celsius.	
	Message *$01,AT?*//<cr><lf>* *$WI,AT=+023.9,C,A*15<cr><lf>*	Comment Query acoustic temperature Sensor response
	Example 2 Query the latest acoustic temperature reading. A valid reading in Kelvin is being acquired.	
	Message *$01,AT?*//<cr><lf>* *$WI,AT=+297.2,K,V*0C<cr><lf>*	Comment Query acoustic temperature Sensor response
	Example 3 - CU AT DFC Mode *$WI,WVC=000.0,333,0,+026.4,C,A*4B*	Comment CUE mode with AT (DFC Mode)
	Example 4 – WV DFC Mode *$WI,WVC=000.0,323,0,+026.3,C,A*4D*	Comment WV response (DFC Mode)

Description	The AT query command returns the current acoustic temperature reading in the selected units. An acoustic temperature reading will be returned even if the sensor is in the process of trying to acquire a valid reading. The acoustic temperature reading is filtered with a one minute time constant by default. The accuracy of the acoustic temperature reading may be affected by the relative humidity of the air surrounding the sensor. See Section 2.9 for further details. Software version V7.5.1 introduced the option for AT (Acoustic Temperature) data to be inserted within the CU & WV output data. A new DF command option (see Section 6.4.9) controls this mode. Caution: The acoustic temperature feature requires calibration at FT Technologies. If the sensor has had a software upgrade to 7.5 (or above) then the data will be uncalibrated and may not comply with the official specification.

6.4.3 AT.2: Set or Query the Acoustic Temperature Units

Command Parameter	AT (units)

Command Syntax		
	SET Sensor:	*$<listenerID>,ATU<units>*<checksum><cr><lf>* *$aa,ATUc*hh<cr><lf>*
	QUERY Sensor:	*$aa,AT?U*hh<cr><lf>*
	Sensor output:	*$<talkerID>,AT=<units>*<checksum><cr><lf>* *$aa,AT=c*hh<cr><lf>*

Parameters	<units>	
	C	The acoustic temperature is to be output in degrees Celsius
	F	The acoustic temperature is to be output.in degrees Fahrenheit
	K	The acoustic temperature is to be output in Kelvin

Examples	Example 1	
	Set the Acoustic Temperature reading output units to degrees Fahrenheit.	
	Message	Comment
	$01,ATUF//<cr><lf>*	Set units to Fahrenheit
	$01,AT?U//<cr><lf>*	Query temperature units
	*$WI,AT=F*5C<cr><lf>*	Sensor response

Description	Use this command to change the measurement units of the acoustic temperature output readings. The available measurement units are degrees Celsius, Fahrenheit and Kelvin.

6.4.4 AT.3 Set or Query the Acoustic Temperature Filter Length

Command Parameter	AT (filter length)

Command Syntax		
	SET Sensor:	*$<listenerID>,ATF<filter length>*<checksum><cr><lf>* *$aa,ATFxxc*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,AT?F*<checksum><cr><lf>* *$aa,AT?F*hh<cr><lf>*
	Sensor output:	*$<talkerID>,AT=<filter length>*<checksum><cr><lf>* *$aa,AT=xxc*hh<cr><lf>*

Parameters	<filter length>	
	00S to 50S, *01M to 10M*	Time constant of the acoustic temperature filter in seconds (S) or minutes (M). Supported settings are 00S (to disable the filter), then ten second increments from 10S up to 50S, then one minute increments from 01M to 10M. (Factory Default Setting = 01M)

Examples	
	Example 1 Set the filter time constant to 40 seconds. Verify that the command has been accepted.
	Message: *$01,ATF40S*//<cr><lf>* — Comment: Set 40s time constant
	Message: *$01,AT?F*//<cr><lf>* — Comment: Query filter time constant
	Message: *$WI,AT=40S*4D<cr><lf>* — Comment: Sensor response
	Example 2 Set the filter time constant to 2 minutes. Verify that the command has been accepted.
	Message: *$01,ATF02M*//<cr><lf>* — Comment: Set 2 minute time constant
	Message: *$01,AT?F*//<cr><lf>* — Comment: Query filter time constant
	Message: *$WI,AT=02M*55<cr><lf>* — Comment: Sensor response

Description	
	Use this command to alter the time constant of the acoustic temperature filter. The filter can be disabled by setting the time constant to zero (00S). Valid time constants are ten second steps from 10S to 50S and then one minute steps from 01M to 10M.

6.4.5 BR: Set or Query the Serial Interface Baud Rate

Command Parameter	BR

Command Syntax	SET Sensor:	*$<listenerID>,BR<baudrate>*<checksum><cr><lf>* *$aa,BRx*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,BR?*<checksum><cr><lf>* *$aa,BR?*hh<cr><lf>*
	Sensor Output:	*$<talkerID>,BR=<baudrate>*<checksum><cr><lf>* *$aa,BR=x*hh<cr><lf>*

Parameters	<baudrate>	
	0	Set the baud rate to 38400 baud
	1	Set the baud rate to 19200 baud
	2	Set the baud rate to 9600 baud (Factory Default Setting)
	3	Set the baud rate to 4800 baud
	4	Set the baud rate to 2400 baud
	5	Set the baud rate to 1200 baud

Examples	Example 1 Set the baud rate to 19200 baud, verify the new setting and send a user reset command to activate the new baud rate	
	Message	Comment
	$01,BR1//<cr><lf>*	Set baud rate to 19200
	$01,BR?//<cr><lf>*	Query baud rate setting
	*$WI,BR=1*2E<cr><lf>*	Sensor Output
	$01,RSU//<cr><lf>*	Send user reset

Description	Use the BR command to change the sensor serial interface baud rate. The new baud rate setting will only come into effect when the sensor is next powered-up or after a Reset command (RSU) has been received. If the baud rate is changed, you will only be able to communicate with the sensor if the host computer's baud rate is set to the same baud rate. If you do not know what the current setting of the sensor baud rate is you will need to try each baud rate in turn until you establish communication.

6.4.6 CF: Set or Query the Wind Compass Settings

Command Parameter	CF(heading)

Command Syntax		
	SET Sensor:	*$<listenerID>,CF<mode>*<checksum><cr><lf>* *$aa,CFc*hh<cr><lf>* *$<listenerID>,CF<heading>*<checksum><cr><lf>* *$aa,CFxxx.x*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,CF?*<checksum><cr><lf>* *$aa,CF?*hh<cr><lf>*
	FT205EV output:	*$<talkerID>,CF=<mode>,<status>,<heading>,<dec>* <checksum><cr><lf>* *$aa,CF=c,c,xxx.x,xxx.x*hh<cr><lf>*

Parameters		
	<heading>	
	000.0 to 359.9	Compass heading in degrees
	<mode>	
	C	Enable calibration mode
	D	Disable compass function
	E	Enable compass function
	MS	Save compass calibration
	<status>	
	D	Compass module either disabled or not present
	V	Valid compass reading
	<dec>	
	000.0 to 359.9	Declination angle. Standard convention requires that westward declination angles are subtracted from magnetic heading in order to derive true heading. Conversely eastward declination angles are added to magnetic heading. However, since the declination angle on the FT205EV is provided in the form 0 to 359.9°, the user must write westerly declination in the form (360 – westerly declination). For example, a westerly declination of 10° would be sent to the FT205EV as 350°.

Examples		
	Example 1 Set the declination angle to 5° East and read the compass heading and declination parameters:	
	Message	Comment
	$01,CF005.0//<cr><lf>*	Set declination angle to 5°
	$01,CF?//<cr><lf>*	Query compass parameters
	*$WI,CF=D,D,005.0,005.0*26<cr><lf>*	FT205EV output
	Example 2 The datum direction of the FT205EV is pointing 40° to the East – set the declination angle a further 5° East and read the compass heading and declination parameters:	
	Message	Comment
	$01,CF005.0//<cr><lf>*	Set declination angle to 5°
	$01,CF?//<cr><lf>*	Query parameters
	*$WI,CF=E,V,045.0,005.0*31<cr><lf>*	FT205EV output
	Example 3 Enable, query and disable the compass:	
	Message	Enable compass
	$01,CFE//<cr><lf>*	Query compass setting
	$01,CF?//<cr><lf>*	FT205EV output (enabled)
	*$WI,CF=E,V,000.0,000.0*35<cr><lf>*	Disable compass
	$01,CFD//<cr><lf>*	

	Example 4 Enable the calibration procedure and save the results *$01,CFC*//<cr><lf>* *$01,CFE*//<cr><lf>* *$01,CFMS*//<cr><lf>*	Begin compass calibration Enable compass calibration Save the compass calibration

Description	Use the CF command to access the compass related features of the FT205EV. See Sections 2.4 & 2.5 for further details about the compass, declination angle and the calibration procedure.

6.4.7 CI: Set or Query the Communication Interface (RS485, RS422, UART)

Command Parameter	CI

Command Syntax	SET Sensor:	*$<listenerID>,CI<interface>*<checksum><cr><lf>* *$aa,CIc*hh<cr><lf>* or *$aa,CIcc*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,CI?*<checksum><cr><lf>* *$aa,CI?*hh<cr><lf>*
	Sensor output:	*$<talkerID>,CI=<interface string>*<checksum><cr><lf>* *$aa,CI=ccccc*hh<cr><lf>*
	QUERY RS422 Transmitter Mode:	*$<listenerID>,CI?2*<checksum><cr><lf>* *$aa,CI?2*hh<cr><lf>*
	Sensor output:	*$<talkerID>,CI=<RS422 tx mode>*<checksum><cr><lf>* *$aa,CI=c*hh<cr><lf>*

Parameters	<interface>	
	8	Set the RS485 interface (Factory Default Setting)
	2A	Set the RS422 interface with the transmitter always enabled.
	2I	Set the RS422 interface with the transmitter disabled when not transmitting.
	U	Set the UART communication interface
	<interface string>	
	RS485	The RS485 Interface is enabled.
	RS422	The RS422 Interface is enabled.
	UART	The UART Interface is enabled.
	<RS422 tx mode>	
	A	The RS422 transmitter is always enabled.
	I	The RS422 transmitter is disabled when not transmitting.

Examples

Example 1

Enable the RS485 interface. Verify that the command has been accepted.

Message	Comment
$01,CI8//<cr><lf>*	Enable RS485
$01,CI?//<cr><lf>*	Query communications interface
*$WI,CI=RS485*3D<cr><lf>*	Sensor response

Example 2

Enable the RS422 interface with the transmitter always enabled. Verify that the interface and transmitter settings.

Message	Comment
$01,CI2A//<cr><lf>*	Enable RS422 with transmitter on
$01,CI?//<cr><lf>*	Query communications interface
*$WI,CI=RS422*30<cr><lf>*	Sensor response
$01,CI?2//<cr><lf>*	Query RS422 transmitter mode
*$WI,CI=A*44<cr><lf>*	Sensor response

Description

Use the CI command to switch between communications interface modes. Only one communications interface can be used at a time, however the sensor is able to receive host commands through any of the three supported interface modes.

When selecting the RS422 interface, the sensor's RS422 transmitter may be set to remain permanently enabled (or only enabled during message transmission).

6.4.8 CU: Set or Query the Continuous Update Setting

Command Parameter	CU

Command Syntax	SET Sensor:	*$<listenerID>,CU<cont.update>,<interval>*<checksum><cr> <lf>* *$aa,CUcxxxxx*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,CU?*<checksum><cr><lf>* *$aa,CU?*hh<cr><lf>*
	Sensor Output:	*$<talkerID>,CU=<cont.update>,<interval>*<checksum><cr> <lf>* *$aa,CU=c,xxxxx*hh<cr><lf>*

Parameters	<continuous update>	
	E	Enabled
	D	Disabled (Factory Default Setting)
	<interval>	
	1 to 59999	interval, in 0.1s increments, between outputs in continuous mode

Examples

Example 1

Set the sensor to output readings automatically every 10 seconds. Verify that the command has been accepted.

Message	Comment
$01,CUE00100//<cr><lf>*	Enable CU mode, rate = 0.1Hz

Example 2

Disable the continuous updating. Verify that the command has been accepted.

Message	Comment
$01,CUD//<cr><lf>*	Disable CU mode
$01,CU?//<cr><lf>*	Query CU mode setting
*$WI,CU=D,00100*40<cr><lf>*	Sensor response

Example 3	Comment
CU Mode example with DFC enabled	(See Section 6.4.9)
$01,CUE00010//*	Enable CU mode (1Hz)
*$WI,WVC=000.0,333,0,+026.4,C,A*4B*	CU DFC Response (1Hz)

Description

Use the CU command to enable or disable the continuous update mode of operation. When continuous update is enabled, the sensor will output wind velocity readings at a rate determined by the <interval> setting.

Each time the continuous update mode is enabled, the required <interval> setting must be sent (even if this has been sent to the sensor previously). When the continuous update mode is enabled, if the sensor is switched-off, when power is reapplied the sensor will automatically resume outputting readings.

Once the sensor has been put into continuous update mode then it becomes a talker only and will not respond to any further commands. To be able to send commands again the continuous mode must be disabled. To achieve this, the CUD (disable continuous update mode) command must be sent within the first four seconds of the power being applied to the sensor. It is possible to modify the four second delay period on the FT205EV sensor, contact FT Technologies for further information.

WARNING: Do not use the continuous update mode if there are other talkers connected to the data bus. Only one active talker is allowed on the data bus at any one time otherwise bus contention will occur

6.4.9 DF: Set or Query the Wind Velocity Data Format

Command Parameter	DF

Command Syntax		
	SET Sensor:	*$<listenerID>,DF<format>*<checksum><cr><lf>* *$aa,DFc*hh<cr><lf>* or *$aa,DFcc*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,DF?*<checksum><cr><lf>* *$aa,DF?*hh<cr><lf>*
	Sensor output:	*$<talkerID>,DF=<format>*<checksum><cr><lf>* *$aa,DF=c*hh<cr><lf>*

Parameters	<format>	
	P	Set the data format to Polar (wind speed and direction) (Factory Default Setting)
	N	Set the data format to NMEA 0183 with wind speed in m/s
	NN	Set the data format to NMEA 0183 with wind speed in knots
	NK	Set the data format to NMEA 0183 with wind speed in km/h
	C	Set the data format to Combined (Polar data & acoustic temperature)

Examples

Example 1
Set the wind velocity output data format to NMEA with wind speed in m/s and verify the new setting.

Message	Comment
$01,DFN//<cr><lf>*	Set format to NMEA (m/s)
$01,DF?//<cr><lf>*	Query format setting
*$WI,DF=N*43<cr><lf>*	Sensor response

Example 2
Set the wind velocity output data format to NMEA with wind speed in knots and verify the new setting.

Message	Comment
$01,DFNN//<cr><lf>*	Set format to NMEA (knots)
$01,DF?//<cr><lf>*	Query format setting
*$WI,DF=NN*0D<cr><lf>*	Sensor response

Example 3
Set the wind velocity data format to 'Combined'

Message	Comment
$01,DFC//<cr><lf>*	Set format to Combined
$01,DF?//<cr><lf>*	Query format setting
*$WI,DF=C*4E<cr><lf>*	Sensor Response = C

Example 4
WV? Command with DFC enabled

	Comment
$01,WV?//*	Query WV wind data
*$WI,WVC=000.0,323,0,+026.3,C,A*4D*	Sensor Response

Example 5
CU Mode example with DFC enabled

	Comment
$01,CUE00010//*	Enable CU mode (1Hz)
*$WI,WVC=000.0,333,0,+026.4,C,A*4B*	CU DFC Response (1Hz)

Description	Use the DF command to set the required format of the wind velocity readings. See command WV (Sections 6.4.29 and 6.4.30) for a description of the sensor output for each of the format types. When a DF Set command is sent to the sensor, a reset of the minimum and maximum readings to their default values is automatically performed. Polar Format: The sensor returns the magnitude of the wind speed (m/s only) and the wind direction (0-359 degrees). NMEA 0183 Format: The sensor returns the wind angle (0-359 degrees, Relative) and wind speed (m/s, knots or km/h). The sensor TalkerID is always set to WI when NMEA format is selected irrespective of any value that may have been set with the ID command.

6.4.10 DG: Query the Run-time Counter

Command Parameter	DG

Command Syntax	SET Sensor:	*N/A*
	QUERY Sensor:	*$<listenerID>,DG?T*<checksum><cr><lf>* *$aa,DG?T*hh<cr><lf>*
	Sensor output:	*$<talkerID>,DG=<counter>*<checksum><cr><lf>* *$aa,DG=xxxxxx*hh<cr><lf>*

Parameters	<counter>	
	000000 to 999999	Holds the number of hours that the anemometer has been in operation during its lifetime.

Examples	Example 1 Query the Run-Time Counter.	
	Message *$01,DG?T*//<cr><lf>* *$WI,DG=012897*CF<cr><lf>*	Comment Query Run-Time Counter Sensor response (12897 hours = 1 year, 5 months, 21 days and 9 hours)

Description	Use the DG command to query the number of operational hours that the anemometer has been in use. The Run-Time Counter is incremented on completion of each full hour that the anemometer has been in use.

6.4.11 DL: Set or Query the Command Delay Interval

Command Parameter	DL

Command Syntax	SET Sensor:	*$<listenerID>,DL<delay>*<checksum><cr><lf>* *$aa,DLxx*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,DL?*<checksum><cr><lf>* *$aa,DL?*hh<cr><lf>*
	Sensor output:	*$<talkerID>,DL=<delay>*<checksum><cr><lf>* *$aa,DL=xx*hh<cr><lf>*

Parameters	<delay> *00 to 20* (delay interval, in 50ms increments) (Factory Default Setting = 01)

Examples	Example 1 Set the command delay interval to 250ms and verify the new setting.	
	Message	Comment
	$01,DL05//<cr><lf>*	Set delay to 250ms
	$01,DL?//<cr><lf>*	Query delay setting
	*$WI,DL=05*02<cr><lf>*	Sensor response

Description	Use the DL command to set the delay interval from when the sensor receives a command to when the command is executed. The DL command is primarily intended for use where a time delay may be required to allow the communications interface to switch from transmit to receive mode. For example, if the delay interval is set to 250ms then the sensor will commence outputting the wind velocity data between 250-300ms after receiving a WV query command. If any further commands are sent to the sensor before the delay interval has elapsed they will be discarded.

6.4.12 ER: Query or Reset the Error Report

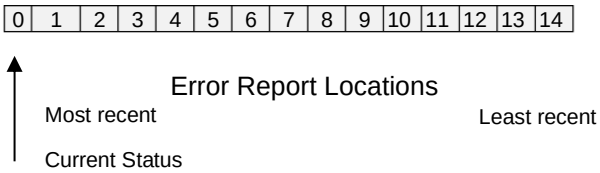
Command Parameter	ER

Command Syntax		
	SET Sensor:	*$<listenerID>,ER<reset>*<checksum><cr><lf>* *$aa,ERc*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,ER?*<checksum><cr><lf>* *$aa,ER?*hh<cr><lf>*
	Sensor output:	*$<talkerID>,ER=<error report>*<checksum><cr><lf>* *$aa,ER=xxxxxxxxxxxxxxx*hh<cr><lf>*

Parameters		
	<reset>	
	R	Resets the historical log section of the error report to all 0's
	<error report>	
	<error report>	Sensor error report string

Examples		
	Example 1	
	Query the error report	
	Message	Comment
	$01,ER?//<cr><lf>*	Query error report
	*$WI,ER=000000000000000*28<cr><lf>*	Sensor response

Description	
	The error report contains information on errors that have occurred during the operation of the sensor. The output string is always comprised of 15 ASCII characters (all shown as '0', ASCII 30(HEX) in the above example).



The first character in the data field represents the current operational status of the sensor. '0' (ASCII 30(HEX)) indicates that the sensor is functioning correctly any other character indicates that an error condition exists. The status is cleared once the ER command is executed.

The next 14 locations contain an historical log of the last 14 errors with the most recent error being recorded in the leftmost position. Each error condition is assigned an ASCII character. The historical log is stored in Flash and is retained when the power is switched off or the sensor software reset.

This report can be sent back to the FT factory for analysis if there are problems with the sensor.

Currently the historical error log is only used for factory diagnostic purposes.

6.4.13 FL.1: Set or Query General Filter Settings

Command Parameter	FL (enable/ disable)

Command Syntax		
	SET Sensor:	*$<listenerID>,FL<filter>*<checksum><cr><lf>* *$aa,FLc*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,FL?*<checksum><cr><lf>* *$aa,FL?*hh<cr><lf>*
	Sensor output:	*$<talkerID>,FL=<filter>*<checksum><cr><lf>* *$aa,FL=c*hh<cr><lf>*

Parameters	<filter>	
	E	Filter enabled (Factory Default Setting)
	D	Filter disabled

Examples	
	Example 1 Enable the filter. Verify that the command has been accepted.
	Message: *$01,FLE*//<cr><lf>* — Comment: Enable filtering
	Message: *$01,FL?*//<cr><lf>* — Comment: Query filter setting
	Message: *$WI,FL=E*40<cr><lf>* — Comment: Sensor response
	Example 2 Disable the filter. Verify that the command has been accepted.
	Message: *$01,FLD*//<cr><lf>* — Comment: Disable filtering
	Message: *$01,FL?*//<cr><lf>* — Comment: Query filter setting
	Message: *$WI,FL=D*41<cr><lf>* — Comment: Sensor response

Description	Use the FL command to enable or disable moving average filtering of the wind speed and wind direction readings (see Section 2.3).

6.4.14 FL.2: Set or Query Filter Lengths

Command Parameter	FL (lengths)

Command Syntax		
	SET Sensor:	*$<listenerID>,FLL<speedLen>,<dirLen>*<checksum><cr><lf>* *$aa,FLLxxxx,xxxx*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,FL?L*<checksum><cr><lf>* *$aa,FL?L*hh<cr><lf>*
	Sensor output:	*$<talkerID>,FL=<speedLen>,<dirLen>*<checksum><cr><lf>* *$aa,FL=xxxx,xxxx*hh<cr><lf>*

Parameters		
	<speedLen> *0001 to 0064*	Sample size of the wind speed filter. Number of previous readings# used to calculate the latest wind speed reading, 0001 is equivalent to disabling the filter (Factory Default Setting = 0016)
	<dirLen> *0001 to 0064*	Sample size of the wind direction filter. Number of previous readings# used to calculate the latest wind direction reading, 0001 is equivalent to disabling the filter; (Factory Default Setting = 0016)

Examples		
	Example 3 Modify the filter's dimensions. Verify that the command has been accepted.	
	Message	Comment
	$01,FLL0001,0032//<cr><lf>*	Set speed filter length to 1 and direction filter length to 32.
	$01,FL?L//<cr><lf>*	Query filter's length settings.
	*$WI,FL=0001,0032*29<cr><lf>*	Sensor response.

Description	
	Use this command to modify the speed and direction filter lengths. When the filter is enabled, speed and direction readings are independently averaged by calculating the mean of the previous number of readings# set by the filter lengths <speedLen> and <dirLen>. # Please note the previous readings filter length by definition includes the most up to date wind reading at position 1. So setting a filter to a length of 0001 gives just the current reading (see Section 2.3). The sensor's internal memory is large enough to retain 64 previous speed and direction readings, allowing for maximum filter length of 6.4 seconds.

6.4.15 FL.3: Set or Query the Selective Filter

Command Parameter	FL (selective filter)

Command Syntax		
	SET Sensor:	*$<listenerID>,FLS<FilterStatus><period>*<checksum><cr><lf>* *$aa,FLScxxx*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,FL?S*<checksum><cr><lf>* *$aa,FL?S*hh<cr><lf>*
	Sensor output:	*$<talkerID>,FL=<FilterStatus>,<period>*<checksum><cr><lf>* *$aa,FL=c,xxx*hh<cr><lf>*

Parameters		
	<FilterStatus>	
	E	Enabled
	D	Disabled
	<Period>	
	000 to 255	Length of validity period (in increments of 0.1 seconds): 000 A single error will trigger the error flag 001 2 consecutive errors will trigger the error flag (0.2 seconds)

Examples		
	Example 1 Query the Selective Filter Status.	
	Message	Comment
	$01,FL?S//<cr><lf>*	Query the Selective Filter status.
	*$WI,FL=E,005*hh<cr><lf>*	Sensor reports it is enabled with a 5 reading (0.5 second) filter.
	Example 2 Enable or Disable the Selective Filter Status.	
	$01,FLSE010//<cr><lf>*	Enable the Selective Filter for up to 10 readings (1 second).
	$01,FLSD//<cr><lf>*	Disable the Selective Filter.

Description	
	In addition to the averaging filter described in Sections 6.4.13 and 6.4.14, the sensor has a feature called the Selective Filter. The scheme allows the user to set a “validity period”, during which the sensor will exclude invalid readings from entering the averaging filter. The output will freeze on the last previous “good” reading and only raise an error flag once the number of bad readings exceeds the validity period. This scheme can be enabled by factory configuration. The filter is turned off by default to match legacy behaviour. Depending on the control system used, this may improve data quality.

6.4.16 HT.1: Query Heater Settings

Command Parameter	HT (Heater Query)

Command Syntax		
	QUERY Sensor:	*$<listenerID>,HT?*<checksum><cr><lf>*
		*$aa,HT?*hh<cr><lf>*
	Sensor output:	*$<talkerID>,HT=<tsp>,<%>,<temp>*<checksum><cr><lf>*
		*$aa,HT=xx,xx,±xx*hh<cr><lf>*

Parameters		
	<tsp> *99*	Heater disabled (factory default setting – cannot be modified)
	<%>	This feature is not applicable to the FT205EV product
	<temp>	*-99 to +99* Read only parameter that returns the current internal temperature of the sensor, In ºC, in the range 00 to ±99ºC

Examples		
	Example 1 Query the Heater settings.	
	Message	Comment
	$01,HT?//<cr><lf>*	Query heater setting
	*$WI,HT=99,00,**+24***3B<cr><lf>*	Sensor Response (+24°C)

Description	
	The HT query command requests the status of the internal heater circuit. Since no heater functionality is included in the FT205EV product, it can only provide details of the internal temperature. In comparison to other sensors in the FT product range, users should be aware the SET heater command is disabled on the FT205EV product. Only the QUERY command is available with limited functionality. Contact FT Technologies for further information about the HT command and the heater performance of various FT wind sensors. Ensure the user application and system does not require heater operation and that the connected system can operate without the legacy functionality of other sensors in the FT range.

6.4.17 ID: Set or Query the Listener & Talker Identifiers

Command Parameter	ID

Command Syntax	SET Sensor:	*$<listenerID>,ID<RxID><TxID>*<checksum><cr><lf>* *$aa,ID=cccc*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,ID?*<checksum><cr><lf>* *$aa,ID?*hh<cr><lf>*
	Sensor output:	*$<talkerID>,ID=<RxID><TxID>*<checksum><cr><lf>* *$aa,ID=cccc*hh<cr><lf>*

Parameters	<RxID>	
	00 to ZZ	The sensor 2 digit listener address identifier (Factory Default RxID = 01)
	<TxID>	
	00 to ZZ	The sensor 2 digit talker address identifier (Factory Default TxID = WI)

Examples

Example 1

Set the sensor listener address identifier to A1 and the talker address identifier to B1. Verify that the command has been accepted.

Message	Comment
$01,IDA1B1//<cr><lf>*	Set address ID's
$A1,ID?//<cr><lf>*	Query ID settings
*$B1,ID=A1B1*6C<cr><lf>*	Sensor response

Note: the ID? command must use the new listener ID otherwise the command will not be recognised.

Description	Use the ID command to set the listener and talker address identifiers. See Section 5.5.4 for information on listener and talker address identifiers.

6.4.18 MM: Reset or Query the Min/Max Recorded Wind Speed

Command Parameter	MM

Command Syntax	SET Sensor:	*$<listenerID>,MM<setting>*<checksum><cr><lf>* *$aa,MMc*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,MM?*<checksum><cr><lf>* *$aa,MM?*hh<cr><lf>*
	Sensor output:	*$<talkerID>,MM=<MinSpeed>,<MaxSpeed>*<checksum><cr><lf>* *$aa,MM=xxx.x,xxx.x*hh<cr><lf>*

Parameters	<setting>	
	R	Resets the min/max readings to their default (<MinSpeed> to 999.9 and <MaxSpeed> to 000.0) until the first reading
	<MinSpeed>	
	000.0 to 999.9	Minimum detected wind speed in current unit (m/s, knots or km/h)
	<MaxSpeed>	
	000.0 to 999.9	Maximum detected wind speed in current unit (m/s, knots or km/h)

Examples	Example 1	
	Query the min/max wind speed readings	
	Message	Comment
	$01,MM?//<cr><lf>*	Query the min/max readings
	*$WI,MM=005.1,034.2*22<cr><lf>*	Sensor response

Description	Use the MM command to query the minimum and maximum wind speed readings that the sensor has recorded since it was last switched on. The minimum and maximum readings are set to their default values when an MMR, an RS or a DF set command is executed.

6.4.19 OS: Set or Query Overspeed Warning Scheme

Command Parameter	OS

Command Syntax	SET Sensor:	*$<listenderID>,OS<mode>*<checksum><cr><lf>* *$aa,OSm*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,OS?*<checksum><cr><lf>* *$aa,OS?*hh<cr><lf>*
	Sensor output:	*$<talkerID>,OS=<mode>*<checksum><cr><lf>* *$aa,OS=m*hh*

Parameters	<Mode>	
	D	Overspeed Warning Disabled
	E	Overspeed Warning Enabled

Examples

Example 1

Enable the Overspeed Warning scheme. Verify that the command has been accepted.

Message	Comment
$01,OSE//<cr><lf>*	Enable the scheme
$01,OS?//<cr><lf>*	Query Overspeed Warning scheme
*$WI,OS=E*56<cr><lf>*	Sensor response

Example 2

Disable the Overspeed Warning scheme. Verify that the command has been accepted.

Message	Comment
$01,OSD//<cr><lf>*	Disable the scheme
$01,OS?//<cr><lf>*	Query Overspeed Warning scheme
*$WI,OS=D*57<cr><lf>*	Sensor response

Description	Use this command to query, enable or disable the Overspeed Warning Scheme (See Section 2.8).

6.4.20 RS: Reset the Sensor

Command Parameter	RS

Command Syntax	SET Sensor:	*$<listenerID>,RS<mode>*<checksum><cr><lf>* *$aa,RSc*hh<cr><lf>*
	QUERY Sensor:	*NA*
	Sensor output:	*None*

Parameters	<mode>	
	S	Reset the sensor, loading saved parameters settings
	U	Reset the sensor, reloading the user parameter settings

Examples	Example 1 Reset the sensor, reloading the last parameter settings	
	Message	Comment
	$01,RSU//<cr><lf>*	Reset sensor, reloading last settings

Description	Use the RS command to reset the sensor software. The sensor will be ready to receive new commands or take readings from a maximum of 2 seconds after any reset command is sent. To restart the software, but continue to use the previous user parameter settings use the RSU command To restart the software, but load the saved parameter settings use the RSS command. See command US (Section 6.4.28) for a description for setting or querying these Saved Parameters.

6.4.21 SN: Query the Serial Number and Platform Version

Command Parameter	SN

Command Syntax	SET Sensor:	NA
	QUERY Sensor:	*$<listenerID>,SN?*<checksum><cr><lf>* *$aa,SN?*hh<cr><lf>*
	Sensor Output:	*$<talkerID>,SN=<SerialNumber>,<PlatformVersion>*<checksum><cr><lf>* *$aa,SN=xxxxx-xxx,xxsss*hh<cr><lf>*

Parameters	<SerialNumber> *00000-000 to 99999-999*	Unique serial number of the sensor
	<PlatformVersion> *00-99*	Platform version (issue) of the sensor design. The 3 spaces after the 2 digit number are reserved for future use.

Examples	Example 1 Read the sensor serial number and platform version	
	Message	Comment
	$01,SN?//<cr><lf>*	Query serial number
	*$WI,SN=09000-130,24 *3E<cr><lf>*	Sensor response

Description	The SN command returns the serial number of the sensor and also the platform version of the sensor. The serial number format starts with a 5 digit batch code, followed by a 3 digit number which identifies a sensor within a particular batch. The overall number is the unique serial number identifier for the sensor.

6.4.22 SV: Query the Software Version

Command Parameter	SV

Command Syntax	SET Sensor:	*NA*
	QUERY Sensor:	*$<listenerID>,SV?*<checksum><cr><lf>* *$aa,SV?*hh<cr><lf>*
	Sensor Output:	*$<talkerID>,SV=<SoftwareVersion>*<checksum><cr><lf>* *$aa,SV=sssx.xss*hh<cr><lf>* *$<talkerID>,SV=<SoftwareVersion>*<checksum><cr><lf>* *$aa,SV=sssx.x.x*hh<cr><lf>*

Parameters	<SoftwareVersion> *1.0 to 9.9* *or* *1.0.0 to 9.9.9*	Software version of the sensor

Examples	Example 1 Read the software version number	
	Message	Comment
	$01,SV?//<cr><lf>*	Query software version
	*$WI,SV= 7.5 *06<cr><lf>*	Sensor response (7.5)
	*$WI,SV= 7.5.1*19<cr><lf>*	Sensor response (7.5.1)

Description	The SV command returns the software version of the sensor. There are three blank spaces between $WI,SV= and the beginning of the software version. For software versions using the format 7.5 two blank spaces will follow. FT may release incremental software versions with the numbering format 7.5.1, in this case there will be no blank spaces following the software version.

6.4.23 UC.1: Set or Query the General User Calibration Settings

Command Parameter	UC (enable/ disable)

Command Syntax		
	SET Sensor:	*$<listenerID>,UC<table>*<checksum><cr><lf>* *$aa,UCx*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,UC?*<checksum><cr><lf>* $aa,UC?*hh<cr><lf>
	Sensor output:	*$<talkerID>,UC=<entries>,<table>,<UCRAMChecksum>, <UCFlashChecksum>*<checksum><cr><lf>* *$aa,UC=nn,x,yyyy,zzzz*hh<cr><lf>*

Parameters		
	<table>	
	E	User Calibration Table enabled
	D	User Calibration Table disabled (Factory Default Setting)
	<entries>	
	nn	Number of calibrated table entries
	<UCRAMChecksum>	
	yyyy	User calibration table RAM copy checksum
	<UCFlashChecksum>	
	zzzz	Saved user calibration table Flash copy checksum

Examples

Example 1

Enable the user calibration table and verify new setting

Message	Comment
*$01,UCE*7E<cr><lf>*	Enable calibration table
*$01,UC?*04<cr><lf>*	Query user calibration table status
*$WI,UC=55,E,5174,5174*70<cr><lf>*	Typical sensor response

Description

Use the UC command to enable or disable the implementation of the user calibration table for calibrating wind speed readings.

The four-digit user calibration table checksum is calculated by summing all table entries over the number of table rows present. The least significant 4 digits of the resulting sum are retained as the table checksum. The user-defined text string is not included in the checksum. Each xx.xx speed value is treated as an integer by ignoring the decimal point.

For example, the table row:
15.00, 14.97 is summed as 1500 + 1497 = 2997. A table sum of 55174 results in the checksum 5174.

If the user calibration table has not been loaded, the number of calibrated table entries (nn) will be 00 and the saved user calibration table Flash copy checksum (zzzz) will be 5535.

When the User Calibration facility is enabled, the uncorrected wind speed indication of the sensor is calibrated according to the stored calibration records, using linear interpolation.

6.4.24 UC.2: Clear User Calibration Table Record

Command Parameter	UC (Erase table)

Command Syntax		
	SET Sensor:	*$<listenerID>,UC<erase>*<checksum><cr><lf>* *$aa,UCCLEAR*hh<cr><lf>*

Parameters		
	<erase>	
	CLEAR	Erases both Flash and RAM copies of user calibration table

Examples		
	Example 1 Erase the user calibration tables and verify	
	Message	Comment
	*$01,UCCLEAR*62<cr><lf>*	Erase calibration tables
	*$01,UC?*04<cr><lf>*	Query user calibration table status
	*$WI,UC=00,D,0000,0000*71<cr><lf>*	Sensor response

Description	
	Use the UCCLEAR command to erase the RAM and saved FLASH copies of the user calibration table. A UCCLEAR is performed before a new user calibration table is loaded (see Section 6.4.25). The user calibration table label is also cleared to 32 ASCII spaces when the UCCLEAR command is sent (see Section 6.4.27).

6.4.25 UC.3: Set User Calibration Table Record

Command Parameter	UC (set & verify record)

Command Syntax		
	SET Sensor Calibration Record:	*$<listenerID>,UCW<Cspeed>,<Uspeed>*<checksum><cr><lf>* *$aa,UCWxx.xx,yy.yy*hh<cr><lf>*
	Verify Last Record:	*$<listenerID>,UC?W*<checksum><cr><lf>* $aa,UC?W*hh<cr><lf>
	Sensor output:	*$<talkerID>,UC=<error code>*<checksum><cr><lf>* *$aa,UC=n*hh<cr><lf>*

Parameters		
	<Cspeed>	
	xx.xx	Corrected speed
	<Uspeed>	
	yy.yy	Uncorrected speed
	<error code>	
	0	Table entry accepted
	1	Error: Sensor speed out of order (latest row speed <previous row speed)
	2	Error: Sensor speed increment less than 0.5ms than previous record
	3	Error: Data entry not allowed (table has not been cleared first)
	4	Error: Bad argument (data format not valid)
	5	Error: User calibration table is full (all 64 rows have been entered)

Examples		
	Example 1 Enter user calibration table record and verify	
	Message	Comment
	*$01,UCW00.90,01.11*48<cr><lf>*	Set a wind speed correction
	*$01,UC?W*53<cr><lf>*	Query if table entry was accepted
	*$WI,UC=0*29<cr><lf>*	Sensor response

Description	
	Use the UCW command to set and verify individual user calibration table records. New records can only be entered if the Calibration table is cleared first (see Section 6.4.24). Up to 64 records can be entered sequentially into the sensor's RAM and verified. Once sufficient records have been loaded, these can be saved to the Flash using the user calibration save command (see Section 6.4.26).

6.4.26 UC.4: Save and Read User Calibration Table

Command Parameter	UC (save and read)

Command Syntax		
	Save Sensor Calibration Record:	*$<listenerID>,UCS*<checksum><cr><lf>* *$aa,UCS*hh<cr><lf>*
	QUERY Saved Sensor Calibration Record:	*$<listenerID>,UC?R<row>*<checksum><cr><lf>* $aa,UC?Rnn*hh<cr><lf>
	Sensor output:	*$<talkerID>,UC=<row>,<Cspeed>,<Uspeed>*<checksum><cr><lf>* *$aa,UC=nn,xx.xx,yy.yy*<cr><lf>*

Parameters		
	<row> *01 – 64*	Calibration table row number
	<Cspeed> *xx.xx*	Corrected speed
	<Uspeed> *yy.yy*	Uncorrected speed

Examples	
	Example 1 Save a new user calibration table from RAM into Flash memory and verify
	Message: Comment
	*$01,UCS*68<cr><lf>*: Save calibration table
	*$01,UC?*04<cr><lf>*: Query user calibration table status
	*$WI,UC=55,E,5174,5174*70<cr><lf>*: Typical sensor response
	Example 2 Read calibration data stored in row 5 of the Flash calibration table
	Message: Comment
	*$01,UC?R05*53<cr><lf>*: Query Flash user calibration record
	*$WI,UC=05,06.00,06.03*1F<cr><lf>*: Typical sensor response

Description	
	Use the UCS command to save a new user calibration table into Flash memory. A user calibration query (see Section 6.4.23) command can then be used to verify that the checksum of the RAM and Flash copies are equal. This demonstrates that the table has been saved without error. Use the UC?R command to verify the data stored in an individual Flash calibration record.

Once the table has been saved into Flash memory, new data and the text string can only be written to it by first clearing the table.

6.4.27 UC.5: Set & Query User Calibration Table Label

Command Parameter	UC (label)

Command Syntax	SET Sensor label:	*$<listenerID>,UCT<text string>*<checksum><cr><lf>* *$aa,UCTxxxxxxxxxxxxxxxxxxxxxxxxxxxxxxxx*hh<cr><lf>*
	QUERY Sensor label:	*$<listenerID>,UC?T*<checksum><cr><lf>* $aa,UC?T*hh<cr><lf>
	Sensor output:	*$<talkerID>,UC=<label32>*<checksum><cr><lf>* *$aa,UC=xxxxxxxxxxxxxxxxxxxxxxxxxxxxxxxx*hh<cr><lf>*

Parameters	*<text string>* *xxxxxxxxxxxxxxxxx* *xxxxxxxxxxxxxx*	Up to 32 upper or lower case alphanumeric ASCII characters (can also include ASCII space, underscore and hyphen characters). Factory default is 32 ASCII spaces.
	<label32> *xxxxxxxxxxxxxxxxx* *xxxxxxxxxxxxxx*	32 ASCII characters, Note: ASCII spaces will be added to entered ASCII string if it is less than 32 characters to form a string of 32 characters.

Examples

Example 1

Set the User Calibration label to “speed offset V03” and verify

Message	Comment
*$01,UCTspeed offset V03*50<cr><lf>*	Set Calibration table label
*$01,UC?T*0C<cr><lf>*	Query Calibration table label
*$WI,UC=speed offset V03*26<cr><lf>*	Sensor response

Description

Use the UCT command to set a User calibration table label. The label can be up to 32 ASCII characters long and include ASCII space, underscore and hyphen characters.

The user calibration table label can be cleared by using the UCCLEAR command. (see Section 6.4.24) This resets the label to 32 ASCII spaces.

UC?T query command will only return a response after the user calibration table has been initialised.

6.4.28 US: Set or Query Saved Parameters

Command Parameter	US

Command Syntax	SET Sensor:	*$<listenerID>,US<setting>*<checksum><cr><lf>* *$aa,USS*hh<cr><lf>*
	QUERY Sensor:	*$<listenerID>,US?*<checksum><cr><lf>* *$aa,US?*hh<cr><lf>*
	Sensor output:	*$<talkerID>,US=<match>*<checksum><cr><lf>* *$aa,US=c*hh<cr><lf>*

Parameters	<setting>	
	S	Copies the User Parameters and saves them as the Saved Parameters.
	<match>	
	P	indicates the User Parameters are the same as the Saved Parameters
	F	indicates the User Parameters are not the same as the Saved Parameters

Examples

Example 1

Set and Verify new user saved parameters

Message	Comment
$01,USS//<cr><lf>*	Set saved parameters
$01,US?//<cr><lf>*	Query the saved parameters
*$WI,US=F*4F<cr><lf>*	Sensor response

Description

There are three copies of Parameters stored in Flash memory namely, User Parameters, Factory Parameters, Saved Parameters respectively. All three copies are initially loaded with the same default settings.

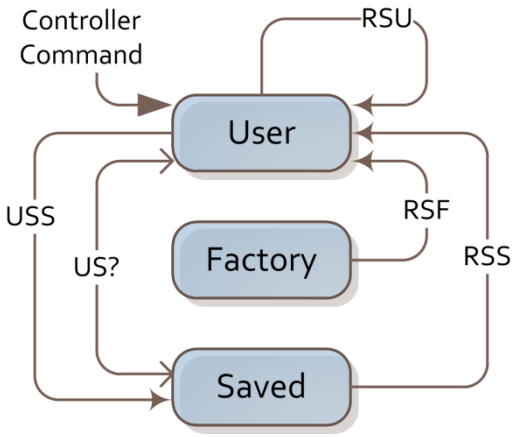


Figure 33: Relationship between the 3 flash copies of Parameter Settings

The User Parameters is the copy that the sensor operates from, at all times. When sending a command to the sensor, it is the User Parameter copy which is updated. The user parameters copy is non volatile so the sensor will keep the last settings when it is powered up again.

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Description continued	The Saved Parameters are created by means of the USS command. This command copies the User Parameters and saves them into a separate area in Flash reserved for the Saved Parameters. The query US command compares item by item the Saved Parameters against the User Parameters and reports any discrepancy; this command could be used after USS to confirm that all of User Parameters have been copied correctly in Saved Parameters. A reset command can be used to load the Saved Parameters back to the User Parameters. See command RSS (Section 6.4.20) for the details of the RSS command. After RSS commands are executed the restored parameters are loaded into RAM, so it is imperative to execute any one of the Set Commands described in Section 6.1.1; executing any one of these commands instructs the sensor to make a non-volatile copy of the newly created User Parameters.

The Command USS should never be done outside of a laboratory or controlled environment. This then ensures that the Saved Parameters copy is not corrupted. Then in the field when changing a User parameter, if a lightning strike occurs exactly at the same time as an attempted change and the User version becomes corrupt there is always a ‘clean’ back up Saved copy of the parameters that can be used to recover the sensor.

6.4.29 WV Polar: Query the Wind Velocity Reading

Command Parameter	WV (Polar)

Command Syntax		
	SET Sensor:	N/A
	QUERY Sensor:	*$<listenerID>,WV?*<checksum><cr><lf>* *$aa,WV?*hh<cr><lf>*
	Sensor output:	*$<talkerID>,WVP=<speed>,<angle>,<status>*<checksum><cr><lf>* *$aa,WVP=xxx.x,xxx,x*hh<cr><lf>* For DFC Mode: *$<talkerID>,WVP=<speed>,<angle>,<status>,<temperature>,<temp.units>,<temp.status>*<checksum><cr><lf>* *$aa,WVP=www.w,xxx,y,zzzz.z,a,b*hh<cr><lf>*

Parameters		
	<speed> *000.0 to 075.0*	Measured wind speed in metres per second
	<angle> *000 to 359*	Measured wind direction in degrees relative to sensor datum
	< status > *0 to Z*	Indicates whether an error condition was detected by the sensor operating system. A status value of 0 indicates no issues have been detected (ASCII 30(HEX)). If the sensor detects an error condition, the status character will be set to 1. If the Overspeed Warning Scheme (see Section 2.8) is enabled and if the sensor detects wind speed above the maximum range, the status flag will be set to 2.
	<Temperature> *-020.0 to +060*	-20°C to +60°C
	<Temp Units> *C*	Degrees Celsius
	<Temp Status> *V or A*	V (Valid temperature data) or (Acquiring data – not yet valid)

Examples	
	Example 1 The following example illustrates the polar wind velocity data format. The example shows the sensor output with a wind speed of 20m/s and a wind angle of 45°. Message — Comment *$01,WV?*//<cr><lf>* — Query the wind velocity *$WI,WVP=020.0,045,0*73<cr><lf>* — Sensor polar response
	Example 2 The following examples illustrates the DFC (Combined) wind velocity data format. The example shows the sensor output with a wind speed of 0m/s, a wind angle of 323° and acoustic temperature of +26.3°C. Message — Comment *$01,WV?*13<cr><lf>* — Query the wind velocity *$WI,WVC=000.0,323,0,+026.3,C,A*4D* — Sensor Response (DFC)

Description	The WV command returns the wind velocity value in the currently selected format. Polar, NMEA 0183 and Combined (polar wind and temperature) data formats are available. Use the DF command, Section 6.4.9, to select the required output format. Polar Format: The sensor returns the magnitude of the wind speed (m/s) and the wind direction (0-359°). NMEA 0183 Format: The sensor returns the NMEA 0183 Wind Speed and Angle sentence MWV (see WV NMEA, Section 6.4.30).

It is important that the status is always monitored. Readings associated with errors should not be treated as valid. It is important that the host computer is able to cope with occasional periods when valid data may be temporarily unavailable.

The status is cleared once the WV command is executed, provided that the error condition does not persist.

6.4.30 WV NMEA: Query the Wind Velocity Reading

Command Parameter	WV (NMEA)

Command Syntax		
	SET Sensor:	N/A
	QUERY Sensor:	*$<listenerID>,WV?*<checksum><cr><lf>* *$aa,WV?*hh<cr><lf>*
	Sensor output:	*$WIMWV,<angle>,<reference,<speed>,<units>,<status>* *<checksum><cr><lf>* *$WIMWV,xxx,R,xxx.x,c,A*hh<cr><lf>*

Parameters		
	<angle>	
	000 to 359	Measured wind direction in degrees relative to sensor datum
	<speed>	
	000.0 to 075.0	Measured wind speed (in metres per second).
	000.0 to 145.8	Measured wind speed (in knots).
	000.0 to 270.0	Measured wind speed (in km per hour).
	<reference>	
	R	Relative (compass disabled)
	T	True (compass enabled)
	<units>	
	M	Indicates the wind speed is presented in metres/second
	N	Indicates the wind speed is presented in knots
	K	Indicates the wind speed is presented in kilometres/hour
	< status >	
	0 to Z	Indicates whether an error condition was detected by the operating system, such as out of range wind speed or incorrect signal level. Any character other than 'A' (ASCII 41(HEX)) = error.

Examples

Example 1

The following example illustrates the NMEA wind velocity data format. The example shows the sensor output in m/s with a wind speed of 20m/s and a wind angle of 45°.

Message	Comment
*$01,WV?*13<cr><lf>*	Query the wind velocity
*$WIMWV,045,R,020.0,M,A*3D<cr><lf>*	Sensor NMEA response

Example 2

The following example illustrates the NMEA wind velocity data format. The example shows the sensor output in knots with a wind speed of 30.6 knots and a wind angle of 9°.

Message	Comment
*$01,WV?*13<cr><lf>*	Query the wind velocity
*$WIMWV,009,R,030.6,N,A*31<cr><lf>*	Sensor NMEA response

Description

The WV command returns the wind velocity value in the currently selected format and units. Polar or NMEA formats are available. Use the DF command, Section 6.4.9, to select the required output format and units.

Polar Format: The sensor returns the magnitude of the wind speed (m/s) and the wind direction (0-359°) (see WV Polar, Section 6.4.29).

NMEA 0183 Format: The sensor returns the NMEA 0183 Wind Speed and Angle sentence MWV. The sensor returns the wind direction (0-359°) and wind speed (m/s, knots or km/h) using the MWV Wind Speed and Angle sentence. The sensor Talker ID is always set to WI when NMEA format is selected, irrespective of any setting that may have been set with the ID command.

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