

Failure Condition, the long term effects on crew workload and the occupants will need to be evaluated.

14.2.1.3 Pilot Reaction Time

The pilot reaction time is considered to be dependent upon the pilot attentiveness based upon the phase of flight and associated duties. The following assumptions are considered acceptable:

- (a) Climb, Cruise, Descent and Holding – Recovery action should not be initiated until three seconds after the recognition point
- (b) Manoeuvring Flight - Recovery action should not be initiated until 1 second after the recognition point
- (c) Approach - the demonstration of malfunctions should be consistent with operation in non-visual conditions. The pilot can be assumed to be carefully monitoring the aeroplane performance and will respond rapidly once the malfunction has been recognized. A reaction time of 1 second between recognition point and initiation of recovery is appropriate for this phase of flight.

NOTE:

- (i) For the final phase of landing (e.g., below 25 m (80 ft)), the pilot can be assumed to react upon recognition without delay.
- (ii) For phases of flight where the pilot is exercising manual control using control wheel steering, if implemented, the pilot can be assumed to commence recovery action at the recognition point.

14.2.1.4. Pilot Recovery

Pilot recovery action should be commenced after the reaction time. Following such delay the pilot should be able to return the aeroplane to its normal flight attitude under full manual control without engaging in any dangerous manoeuvres during recovery and without control forces exceeding the values given in CS 25.143 (d). During the recovery the pilot may overpower the automatic pilot or disengage it.

For the purpose of determining the minimum height at which the autopilot may be used during an approach, or for height loss assessments, a representative recovery appropriate to the aeroplane type and flight condition should be performed. This manoeuvre should not lead to an unsafe speed excursion to resume a normal flight path. An incremental normal acceleration in the order of 0.5 g is considered the maximum for this type of manoeuvre.

14.2.2 Takeoff

The primary concern for the takeoff phase of flight is the effect of the worst case Failure Condition, identified by the Safety Assessment, on the net flight of the aeroplane after takeoff and the aeroplane's attitude and speed during climbout. The effects should be evaluated in the pitch up, pitch down and bank as applicable.

If the FGS provides on runway guidance for takeoff, the effect of the failures on that takeoff guidance should be assessed in accordance with CS AWO Subpart 4.

14.2.3Climb, Cruise, Descent and Holding

Where the Safety Analysis identifies a Failure Condition requiring flight/simulator evaluation with pilot assessment, the height loss should be established in accordance with the method described in the flight test procedures – see [AMC No.2 to CS 25.1329](#), section 4.2.3.3.

14.2.4Manoeuvring

Where the Safety Analysis identifies a Failure Condition that has a dynamic effect on the roll control of the aeroplane, the Failure Condition should be introduced at the bank angle for normal operation. The bank angle should not exceed 60 degrees when the pilot recognition and recover times identified above are applied.

14.2.5Approach

A discussion of the operational considerations for approach operations is contained in Section 14.3. This section identifies test criteria to support those considerations. The safety assessment process should identify the demonstration of specific Failure Conditions during the approach.

The fault demonstration process during approach should include the four phases identified in Section 14.2.1. The Failure Condition should be inserted at a safe but representative height. The deviation profile should be identified and applied as indicated in the later sections.

14.2.5.1 Approach with Vertical Path Reference

Approach with vertical path reference includes xLS and RNAV operations.

a) xLS (ILS, MLS, GLS)

ILS and MLS operations are typically conducted on instrument approach procedures designed in accordance with United States TERPS or ICAO PANS-OPS criteria, or equivalent. These criteria together with ICAO Annex 14 are generally intended to take into account obstacles beneath a reference obstacle identification surface. It is expected that the same or equivalent criteria will be applied to GLS operations. Hence, in assessing the implication of the effect of failures during autopilot operations a reference 1:29 slope penetration boundary has been applied against the deviation profile to identify an appropriate altitude for continued autopilot operation. The 1:29 slope has been found to provide an acceptable margin above obstacles on an approach.

The worst case Failure Condition identified by the Safety Assessment (see Section 13.4) should be demonstrated against the deviation profile criteria and a Minimum Use Height (MUH) established (See [AMC No.2 to CS 25.1329](#), Section 4.2.3.2).

b) RNAV

For RNAV coupled approach operations, a vertical flight path similar to an xLS flight path will be used (e.g., 30 path starting 15 m (50 ft) above the threshold). However, due to sensor characteristics it is assumed that RNAV operations will be conducted with a DA(H) or MDA(H) that is higher than an equivalent MUH on an xLS approach to

the same runway. Further, for this type of operation it should be noted that the MUH is always in the visual segment of the approach, where it is assumed that the failure recognition and recovery are conducted with the pilot having established outside visual reference.

In order to derive only one MUH value for simplicity of use, it is assumed that the effects of failure on the autopilot in RNAV operation are no worse than for the xLS operation, and no further determination or demonstration is required. However, the applicant should show that due account has been taken in the Safety Assessment of the differences between the RNAV and xLS inputs to the autopilot (e.g. barometric altitude input, FMS position and guidance commands, and their failure effects). If these effects can be bounded or otherwise reconciled, then the xLS demonstrated MUH might also be considered applicable to RNAV operations.

If these effects cannot be bounded or accounted for within those for the xLS operation, the MUH should be determined in accordance with an Approach Without Vertical Path Reference – see below.

14.2.5.2 Approach Without Vertical Path Reference

For an approach without vertical path reference (e.g., VOR, NDB, localizer only) the FGS mode of operation is typically vertical speed/flight path angle (i.e. a cruise mode). The worst case Failure Condition for this type of mode should be demonstrated in the approach configuration, and an appropriate height loss established in accordance with the method described in [AMC No.2 to CS 25.1329](#), Section 4.2.3.3.

14.2.5.3 Steep Approach

In support of an approval to use the FGS on glidepath angles of greater than 3.5 degrees (see Section 14.1.3.4) an assessment should be made of the effects of failure conditions for this type of operation. For the use of autopilot, an appropriate MUH should be established in accordance with the deviation profile method described in Section 14.2.5. For this assessment, the obstacle plane associated with a nominal 3-degree glidepath angle (1:29 slope) should be adjusted according to the maximum approach angle, for which approval is sought.

14.2.6 Specific Conditions

The following are failure conditions that should be considered as part of the FGS evaluation program:

- Engine Failure during approach - continue approach to DA(H)/MDA(H)
- The effect of potential fuel imbalance
- Aeroplane System Failures (as necessary – requiring specific flight evaluation), e.g.,
 - Hydraulics
 - Electrical
 - Flight Controls

— FGS related Sensors

The probability of failure of a FGS element to disengage when the quick disengagement control is operated should be shown to be acceptable by the Safety Analysis process. If credit is to be taken for acceptable continued manual operation with the FGS elements remaining engaged i.e. without operating any of the other disengagement controls, then a flight demonstration should be conducted though approach, landing and rollout.

14.3 Criteria Supporting the Operational Use of an Autopilot

The criteria contained in this section are intended to identify how the functional capability of the FGS, established during the certification, can be utilized to support typical flight operations. The criteria are based on experience gained from certification programs and functionality provided by traditional systems. A FGS providing non-traditional functionality, using new or novel technology, and/or implementation techniques, may require additional criteria to be established.

14.3.1 Autopilot Operations in close proximity the ground

The minimum engagement point for the autopilot after takeoff and the minimum use of the autopilot during approach should take into consideration the effect of:

- Failures and their effects (i.e., Failure Conditions),
- Fault-free performance,
- Any specific operational considerations and/or mitigation.

During low visibility operations, multiple redundant autopilot channels may be used and the effect of any autopilot failures on the flight path may be eliminated, or substantially minimized, by the protection provided by that redundancy. The following considerations apply primarily to single channel operations where performance or integrity aspects may require further consideration. See also Section 13.5.2, which identifies specific considerations relating to autopilot operations close to the ground in the presence of failures.

14.3.1.1 Autopilot Engagement Altitude or Height after Takeoff – Failure Effects

The potential deviation of the aeroplane from the desired flight path due to the effect of a Failure Condition may necessitate delaying the engagement of an autopilot to an acceptable height above the departure runway.

To support this determination, if an autopilot Failure Condition, or Failure Conditions, are identified that will cause a significant deviation below the intended vertical flight path, the worst-case deviation profile should be identified. This profile and the recovery of the aeroplane should not result in penetration of the net flight path as defined in [CS 25.115](#). If the Failure Condition(s) has a neutral effect on the flight path but has implications for speed control during takeoff, the acceptability of cues for the flight crew detection of the condition should be made. The effect of any Failure Condition relating to the bank angle of the aeroplane should also be assessed. In all of the above, account should be taken of operating the aeroplane at the WAT limit.

The minimum engagement height will typically be established based on the greater of the following considerations:

- The lowest altitude or height where the flight crew could reasonably be assumed to engage the autopilot. Consideration should be given to normal flight crew tasks during rotation and lift-off (typically 30 m (100 ft) or greater).
- Any allowance for the acceptability of the performance of the autopilot during the basic engagement/mode transition.
- The lowest altitude or height consistent with the response of the aeroplane to any identified autopilot Failure Condition(s).
- Activation of stall identification system (e.g. stick pusher) armed (if installed).

If the response to the worst-case failure condition causes a significant transition below the intended vertical flight path, the deviation information should be provided in the AFM.

14.3.1.2 Autopilot Engagement during Approach

The potential deviation of the aeroplane from the desired flight path due to the effect of a Failure Condition may necessitate the disengagement of an autopilot at an appropriate height on the approach to landing.

The operational minimum engagement height will be established based on the following considerations:

- the altitude or height at which the performance of the automatic control is no longer acceptable,
- the lowest altitude or height consistent with the response of the aeroplane to a subsequent autopilot failure,
- any specific operational consideration.

The following paragraphs provide assessment criteria for operations that have guidance to the runway threshold, and for those that do not.

14.3.1.2.1 Approach with Vertical Path Reference – Failure Effects

Approaches with vertical path reference can include xLS (i.e., ILS, MLS and GLS) or RNAV. Operations using xLS, can be assumed to be conducted with respect to a flight path prescribed or established as an integral part of navigation service provided by the State of the airport. RNAV approach operations will be conducted using an onboard database that provides a navigation flight path to the runway.

The operational consideration for this type of operations relates an assessment of the adequacy of continued use of the autopilot in maintaining the desired vertical flight path. Considerations include the lowest altitude consistent with the response of the aeroplane to an autopilot failure.

To support this determination, if an autopilot Failure Condition, or Failure Conditions, is identified that causes a significant transition below the intended vertical flight path, the worst-case deviation profile should be identified using the method identified in Section 14.2.5.1. If the Failure Condition(s) has a neutral effect on the flight path, the acceptability of cues for the flight crew detection of the condition should be made. The effect of

any Failure Condition relating to the bank angle of the aeroplane should be assessed.

For the purpose of the airworthiness assessment, the vertical flight path an xLS and RNAV approach can be assumed to be a flight path of three degrees that passes through the runway threshold at an altitude of 15 meters (50 ft). Considerations for steep approaches are provided in a preceding section.

The vertical flight path control for an xLS approach will be made with reference to the path defined by the navigation service. The RNAV vertical flight path will typically be conducted with reference to barometric altitude. An appropriate adjustment to the minimum use height may be appropriate to take into account the vertical accuracy of RNAV operations.

NOTE: Any operational considerations such as temperature effect compensation should be considered as part of the operational authorization.

The Minimum Use Height can be determined using the method identified in [AMC No.2 to CS 25.1329](#), Section 4.2.3.2.

14.3.1.2.2 Approach without Vertical Path Reference

Flight operations with no vertical path reference are conducted with an appropriate visual segment for final approach path. In the interest of providing appropriate automatic control to assist in a stabilized approach, the minimum use of the autopilot should be consistent with the performance needed for the descent (e.g., vertical speed/flight path angle) and the pilot detection and recovery from an autopilot failure.

To support this determination, if an autopilot Failure Condition, or Failure Conditions, is identified that causes a significant transition below the intended vertical flight path, the worst-case deviation profile should be identified. If the Failure Condition(s) has a neutral effect on the flight path but has implications for speed control during takeoff, the acceptability of cues for the flight crew detection of the condition should be made. The effect of any Failure Condition relating to the bank angle of the aeroplane should be assessed.

For FGS that are failure protected (i.e., fail passive), the minimum engagement height will typically be no lower than 15 m (50 ft) above runway elevation. However, when determining this limitation, account should be taken of the handling task presented to the pilot when regaining manual control, especially in limiting crosswind conditions.

For FGS that are not failure protected (i.e., not fail-passive), the demonstrated minimum use height will typically be established based on the greater of the following considerations:

- a. 15 m (50 ft) above runway elevation
- b. Two times the Height Loss for the aeroplane as a result of any identified autopilot Failure Condition(s) using the method identified in [AMC No.2 to CS 25.1329](#), Section 4.2.3.3.

14.3.1.3 Circling Approach

For the purposes of this AMC, circling approaches may be considered to have three visual segments associated with the approach; a segment at or above the minimums prescribed by the procedure that parallel the runway in the opposite direction of the landing runway, a turning segment to align with the runway that can be level or partially descending, and a final descending segment to landing. Operationally, the autopilot may remain engaged even after leaving the minimum altitude (MDA(H)) for safety and flight crew workload relief reasons. This operational procedure should be balanced against unacceptable performance or failure characteristics. As this procedure is in the visual segment, no specific constraints for the use of the autopilot are considered necessary for this phase of flight unless specific unacceptable performance or failure characteristics related to circling approach are identified during the certification program.

14.3.2 Climb, Cruise, Descent, and Holding

The value of the use of the autopilot in providing flight crew workload relief in climb, cruise, descent and holding phases of flight should be balanced against the failure characteristics of the autopilot. No specific constraints for the use of the autopilot are considered necessary for these phases of flight unless specific unacceptable performance or failure characteristics are identified during the certification program, related to climb, cruise, descent or holding.

14.3.3 Manoeuvring

No specific constraints for the use of the autopilot are considered necessary for manoeuvring flight unless unacceptable performance or failure characteristics are identified during the certification program. Section 14.2.4 provides assessment criteria for manoeuvring flight for autopilot failures.

14.4 Automatic Disengagement of the Autopilot

Automatic disengagement of the FGS will occur for several reasons such as system failures, sensor failures, unusual accelerations, etc. The automatic disengagement characteristics of the FGS should be investigated throughout the flight envelope. These disengagement cases should be analysed to determine the ones requiring demonstration during the test program. For each disengagement, the transients, warnings, and pilot workload for recovery should be evaluated, and compliance with [CS 25.1329](#) (d) and (e) should be verified. The use of simulation is recommended for all conditions that are expected to result in significant transients.

14.5 Assessment of Human Factors Considerations

The evaluation, demonstration and testing should assess the acceptability of the human-machine interface with the FGS and the potential for flight crew errors and confusion concerning the behaviour and operation of the FGS, based on the criteria described in earlier Sections.

The evaluation of normal and non-normal FGS operations should include the representative range of conditions in terms of crew mental or physical workload, required crew response timeliness, or potential for confusion or indecision. The set of test cases should represent operationally relevant scenarios and the assumptions about pilot training and skill level should be documented.

Flight evaluation during certification is a final assessment and is intended to validate the design. Prior evaluations are typically conducted in a variety of ways and at different levels of fidelity in order to finalize the design. These may include:

- Engineering evaluations and task analyses, including cognitive and physical tasks;
- Mock-up evaluations and demonstrations;
- Part-task evaluations and demonstrations;
- Simulator evaluations, demonstrations, and tests; and
- Engineering flight evaluations, demonstrations, and tests.

The data and/or experience from such evaluations may be useful for credit to establish FGS compliance with regulations having human factors considerations. In some cases, certification credit or demonstration of compliance using simulations cannot be granted due to inability to find simulation conformity. In such cases, certification authorities may consider that less flight testing may be required to show compliance if the simulation evaluations have added confidence with respect to the reduced potential for crew error and confusion and other human factors attributes of the pilot/FGS interface. Also, applicants have successfully used comparisons to previously certificated designs to obtain such credit (although such credit is not assured). Additional testing may be warranted, e.g., for new FGS flight crew interface designs or functions.

In many cases the evaluation, demonstration and test scenarios, including failures and environmental events, will determine whether the data should be obtained in simulation or in flight, because of safety considerations or unavailability of the necessary environmental conditions. In some of these cases a very high fidelity simulation will be needed. In addition to the simulation validation considerations identified in Section 14.1.4.2, the simulation used may need to include the following features, depending on the functionality of the FGS:

- Physical implementation of flight deck controls, displays, indicators and annunciators for all flight crew positions that are relevant to the objectives of the evaluation.
- Adequate emulations of relevant equipment (hardware and software function, including capability to introduce failures) should be incorporated in the simulation.
- Weather simulation including gusts, turbulence, windshear and visibility.
- Representation of the operational environments, including interaction with air traffic services, day/night operations, etc, as relevant to the functions and pilot tasks being evaluated
- Data collection capabilities

Simulator evaluations and tests are intended to generate objective and/or subjective data. It may not always be possible or necessary to obtain quantifiable measurements of flight crew performance, even with high fidelity flight or simulation evaluation, demonstration, or test scenarios. In these cases, evaluation procedures should be based on the use of structured, subjective methods such as rating scales, questionnaires and/or interviews. When there is dependence on this type of data, evaluations should consider multiple data collection techniques with an appropriate number of pilot evaluators.

In order to provide sound evaluations, pilots should be trained appropriately on the FGS system operation and procedures. They should also have experience in the kinds of

operation and aircraft types for which the FGS is intended, be familiar with the intended function of the FGS, its operational and design philosophy, and how this philosophy fits with the overall flight deck and its operational and design philosophy.

Rationale should be provided for decisions regarding new or unique features in a design. It should be confirmed that the data resulting from the evaluations support acceptability of any new or unique features.

The certification planning documentation should describe the means to show compliance of the Human Factors-related considerations of the FGS, with this AMC.

15 AEROPLANE FLIGHT MANUAL (AFM)

The following sections provide guidance on material to be provided in the Aeroplane Flight Manual (AFM) to ensure that the appropriate information related to FGS operation is translated into air carrier operations. For additional guidance, note that AMC 25.1581 addresses requirements of the AFM for Large Aeroplanes and distinguishes between those aircraft that are used in Commercial Air Transportation and those that are not.

The terminology used in the AFM should be consistent with the intended operational use.

Appropriate AFM information related to low-visibility operations is addressed in CS-AWO Subparts 1-4.

15.1 Information Supporting Operational Use of the Autopilot

The airworthiness certification process will assess the effect of autopilot Failure Conditions as identified in Sections 13 and 14. If a specific Minimum Use Height (MUH) is necessary, then the height should be provided in the Limitations section of the AFM. If the design is such that the effects of Failure Condition(s) do not require establishment of a MUH, then the pertinent deviation profile or height loss information should be provided in the Normal or Non-normal section of the AFM, as applicable.

If MUH or a Height Loss value is applicable, it should be specified as follows:

- (a) Takeoff - Autopilot Engagement Altitude or Height.

NOTE: If minimum engagement altitude(s) or height(s) are not specified, then “maximum displacement deviation” information from a pertinent takeoff flight path and approach profile should be provided in the AFM Normal Procedures section, or in the associated Flight Crew Operation Manuals (FCOM).

- (b) Cruise – Height Loss

- (c) Approach - MUH or Height Loss

- i) Approach – with Vertical Path Reference

- the MUH should be determined based on clearance above a 1:29 plane using the Deviation Profile Method.

- ii) Approach – without Vertical Path Reference

- the Height Loss should be determined using the Height Loss Method

15.2 Limitations

The Limitations section of the AFM presents those FGS operating limitations appropriate to the aeroplane model as established in the course of the type certification process, and

as necessary (Ref. [CS 25.1581\(a\)\(1\)](#) and [CS 25.1583](#)). FGS operational limitations (should any exist) should specify, any configuration/envelope restrictions, if and as applicable.

15.3 Non-normal/Emergency Procedures

The AFM should include Non-normal or Emergency procedures appropriate to the FGS identified during the certification program (Ref. [CS 25.1581\(a\)\(1\)](#), [CS 25.1585\(a\)\(2\)](#) and [CS 25.1585\(a\)\(3\)](#)).

15.4 Normal Procedures

The normal procedures for use of the FGS should be documented in the AFM or FCOM, as appropriate. These procedures should be demonstrated during the type certification process.

In lieu of specification of minimum engagement altitude(s) or height(s) (see Section 15.1 above)), the AFM may alternately specify “maximum displacement deviations” from a specified takeoff flight path, or from a specified approach profile. This information may be based on typical departure or approach flight paths suited for the aircraft type and for failure conditions that are determined applicable to the type of FGS system and modes suitable for use.

The flight manual should include any necessary procedures for the use of the flight guidance system in icing conditions (including severe icing conditions). In particular, the procedures should include any necessary changes in operating speeds required either operationally or as a result of relevant design features of the speed protection function of the FGS; e.g., variations in minimum speeds as a function of de/anti-icing system selection; speed increments during approach and landing in turbulence.

15.4.1 Aircraft with Published Flight Crew Operation Manuals

The AFM’s for aircraft for which the manufacturer has published a FCOM should contain essential information on normal operating procedures that are considered “peculiar” to the operation of the FGS for the aircraft type or are otherwise necessary for safe operation (Ref. [CS 25.1581\(a\)\(2\)](#) and [CS 25.1585\(a\)\(1\)](#)). FGS description and integration with the overall flight deck design philosophy; specification and operational procedures that are normally associated with flight guidance systems should be made available for inclusion in the FCOM.

If applicable, a FCOM may contain the “maximum displacement deviation” information described in Section 15.1, above, in either numeric or graphic form.

15.4.2 Aircraft without Published FCOM’s

For aircraft that rely on the AFM as the sole operating manual, the AFM must contain operating information sufficient for flight crew reference (Ref. [CS 25.1581\(a\)\(2\)](#)). FGS description and integration with the overall flight deck design philosophy, specification and operational procedures that are normally associated with flight guidance systems should be made available so that an appropriately trained flight crew may operate the FGS under normal conditions.

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