in the case of unusually prolonged manoeuvres, provided that the reduced control forces would not be hazardous.

(f) If the use of this mode for takeoff and landing is to be permitted, it should be shown that:

i) Sufficient control, both in amplitude and rate is available without encountering force discontinuities;

ii) Reasonable mishandling is not hazardous (e.g., engaging the automatic pilot while the elevators or ailerons are held in an out-of-trim position);

iii) Runaway rates and control forces are such that the pilot can readily overpower the automatic pilot with no significant deviation in flight path; and

iv) Any lag in aircraft response induced by the CWS mode is acceptable for the intended manoeuvre.

(g) It should not be possible to revert to the CWS mode by applying an input to the control column or wheel unless the autopilot is in a capture mode (e.g., altitude capture, localizer capture). When the force is released, the autopilot should return to the previously engaged capture mode or to the track mode.

NOTE:CWS, if it is provided, is considered to be an autopilot mode, as it is a specific function of the FGS. However, during CWS operation, it is the pilot and not the autopilot that is in control of the aircraft. Operationally, CWS is identical to the pilot flying the aeroplane during manual flight. In both cases, it is the pilot who is in actual control of the flight path and speed of the aeroplane. The only difference is the mechanization of how the actual flight control surfaces are moved. No "automatic" FGS commands are involved during CWS operation. Therefore, sections in this AMC such as those which discuss Speed Protection and performance objectives should be applied to only those autopilot modes with which the FGS is in control of the flight path of the aeroplane and should not be applied to CWS.

NOTE:The terminology "Control Wheel Steering" is currently used by industry to describe several different types of systems. This section is meant to apply only toward those systems that are implemented in a manner as described above. For comparison, several other functions that are similar in nature, but functionally very different, to CWS are described below. This section does not apply to functions of these types.

— Touch Control Steering (TCS) is a function that is available on many business and commuter aircraft. With TCS, a pilot is able to physically disengage the autopilot servos from the flight control system, usually by pushing and holding a button on the control wheel, without causing the autopilot system itself to disengage or lose its currently selected modes. The pilot may then manoeuvre the aeroplane as desired using the aircraft's flight control system (i.e., the autopilot servos are not part of the control loop). The pilot is then able to reconnect the autopilot servos to the flight control system by releasing the TCS button. Using the new orientation of the aircraft as a basis, the autopilot will then reassume control the aeroplane using the same mode selections as were present before the selection of TCS. This type of system on some aircraft is also sometimes referred to as Control Wheel Steering.

— Also different from CWS is what is referred to as a "supervisory override" of an engaged autopilot. With this function, a pilot is able to physically overpower an engaged autopilot servo by applying force to the flight deck controls. With a supervisory override, the autopilot does not automatically disengage due to the pilot input. This allows the pilot to position the aeroplane as desired using the flight deck controls without first disengaging the autopilot. When the pilot releases the controls, the autopilot reassumes control of the aeroplane using the same mode selections as were present before the supervisory override.

— The descriptions of TCS and supervisory override are intended to be generic. Specific implementations on various aircraft may vary in some aspects.

11.7 Special Considerations for the Integration of Fly-By-Wire Flight Control Systems and FGS

Speed protection features may be implemented in the fly-by-wire flight control system. However, if speed protection is also implemented within the FGS, it should be compatible with the envelope protection features of the fly-by-wire flight control system. The FGS speed protection (normal flight envelope) should operate to or within the limits of the flight control system (limit flight envelope).

Information should be provided to the flight crew about implications on the FGS following degradation of the fly-by-wire flight control systems.

12 FLIGHT GUIDANCE SYSTEM INTEGRATION

Throughout the preceding sections of the document, flight guidance systems and functions have been considered as being separate and distinct from other systems and functions on the aircraft. It is recognized that in complex aircraft designs, the flight guidance functions are closely integrated with other avionics functions, and that the physical integration of these systems, may have a bearing on how aeroplane level safety is assessed. The following paragraphs provide guidance on the likely FGS system integration issues found in more complex aircraft system designs, and the interfaces which should be considered within the bounds of demonstrating the intended function, performance and safety of the FGS.

12.1 System Integration Issues

Integration of other aircraft systems with the FGS has the potential of reducing the independence of failure effects and partitioning between functions. This is particularly the case where hardware and software resources are shared by different systems and functions (e.g., aircraft data highway and Integrated Modular Avionics (IMA) architectures). In addition to considering the reliability and integrity aspects of the FGS as a separate system, it may be necessary to address the effects of FGS failures with respect to fault propagation, detection, and isolation within other systems. The overall effect on the aircraft of a combination of individual system failure conditions occurring as a result of a common or cascade failure, may be more severe than the individual system effect. For example, failure conditions classified under CS 25.1309 as Minor or Major by themselves may have Hazardous effects at the aircraft level, when considered in combination. With regard to isolation of failures, and particularly combination failures, the ability of the alerting system to provide clear and unambiguous information to the flight crew, becomes of significant importance. See also Section 13, Safety Assessment.

Complex and highly integrated avionics issues present greater risk for development error. With non-traditional human-machine interfaces, there is also the potential for operational flight crew errors. Moreover, integration of systems may result in a greater likelihood of undesirable and unintended effects.

Within the FGS, where credit is taken for shared resources or partitioning schemes, these should be justified and documented within the System Safety Analysis. When considering the functional failures of the system, where such partitioning schemes cannot be shown to provide the necessary isolation, possible combination failure modes should be taken into account. An example of this type of failure would be multi-axis active failures, where the control algorithms for more than one axis are hosted on a single processing element. Further, the functional integration of control functions such as control surface trimming, yaw channel, and stability augmentation, while not strictly FGS, should be considered.

12.2 Functional Interfaces

In its simplest form, the FGS may be considered as interfacing with sensors that provide the necessary inputs to enable computation of its various functions. Typically, these sensors will include air and inertial data, engine control, and navigation sensors such as ILS, VOR, and DME. In the case of engine control, a feedback loop may also be provided. The FGS may also be considered as providing inner loop closure to outer loop commands. The most common interface is with the FMS, which provides targets for lateral and vertical navigation in the form of steering orders.

In demonstrating the intended function and performance of both the FGS and systems providing outer loop commands, the applicant needs to address potential inconsistencies between limits of the two (e.g., with basic FGS pitch and bank angle limits). Failure to address these points can result in discontinuities, mode switching, and reversions, leading to erroneous navigation and other possible safety issues (e.g., buffet margin at high altitude). Similar issues arise in the inner loop, across the functional interface between FGS and flight controls. In fly-by-wire aircraft, the loss of synchronization between the two can result in mode anomalies and autopilot disengagement.

The applicant should demonstrate the intended function and performance of the FGS across all possible functional interfaces. The alerting system should also be assessed to ensure that accurate and adequate information is provided to the flight crew when dealing with failures across functional interfaces.

13 SAFETY ASSESSMENT

CS 25.1309 defines the basic safety specifications for airworthiness approval of aeroplane systems and AMC 25.1309 provides an acceptable means of demonstrating compliance with this rule. This section provides additional guidance and interpretive material for the application of CS 25.1309 to the approval of FGS.

A Safety Analysis document should be produced to identify the Failure Conditions, classify their hazard level according to the guidance of AMC 25.1309, and establish that the Failure Conditions occur with a probability corresponding to the hazard classification or are mitigated as intended. The safety assessment should include the rationale and coverage of the FGS protection and monitoring philosophies employed. The safety assessment should include an appropriate evaluation of each of the identified FGS Failure Conditions and an analysis of the exposure to common mode/cause or cascade failures in accordance with AMC 25.1309. Additionally, the safety assessment should include justification and description of any functional partitioning schemes employed to reduce the effect/likelihood of failures of integrated components or functions.

There may be situations where the severity of the effect of a failure condition identified in the safety analysis needs to be confirmed. Laboratory, simulator or flight test, as appropriate, may accomplish the confirmation.

It is recommended that the Safety Analysis plan is coordinated with the regulatory authority early in the certification program.

13.1 FGS Failure Conditions

One of the initial steps in establishing compliance with CS 25.1309 for a system is to identify the Failure Conditions that are associated with that system. The Failure Conditions are typically characterized by an undesired change in the intended function of the system. The Failure Condition statements should identify the impacted functionality, the effect on the aeroplane and/or its occupants, specify any considerations relating to phase of flight and identify any flight crew action, or other means of mitigation, that are relevant.

Functionality - the primary functions of a FGS may include:

— automatic control of the aeroplane's flight path utilizing the aeroplane's aerodynamic control surfaces,

— guidance provided to the flight crew to achieve a particular desired flight path or manoeuvre, through information presented on a head-down or head-up display system, and

— control of the thrust applied to the aeroplane.

Dependent upon the functionality provided in a specific FGS, the failure conditions could potentially impact the following:

— the control of the aeroplane in the pitch, roll and directional axes,

— the control of thrust,

— the integrity and availability of guidance provided to the flight crew,

— the structural integrity of the aeroplane,

— the ability of the flight crew to cope with adverse operating conditions,

— the flight crew's performance and workload,

— the safety of the occupants of the aeroplane.

NOTE: The safety assessment of a FGS for use in supporting takeoff, approach and landing operations in low visibility conditions is further addressed in CS-AWO.

13.2 Type and Severity of Failure Conditions

The type of the FGS Failure Conditions will depend, to a large extent, upon the architecture, design philosophy and implementation of the system. Types of Failure Conditions can include:

— Loss of function – where a control or display element no longer provides control or guidance

— Malfunction – where a control or display element performs in an inappropriate manner which can include the following sub-types:

a) Hardover – the control or display goes to full displacement in a brief period of time – the resultant effect on the flight path and occupants of the aeroplane are the primary concern.

b) Slowover - the control or display moves away from the correct control or display value over a relatively long period of time – the potential delay in recognizing the situation and the effect on the flight path are the primary concern.

c) Oscillatory - the control or display is replaced or augmented by an oscillatory element – there may be implications on structural integrity and occupant well being.

Failure Conditions can become apparent due to failures in sensors, primary FGS elements (e.g., autopilot, flight director, HUD), control and display elements (e.g., servos, primary flight displays), interfacing systems or basic services (e.g., electrical and hydraulic power).

The severity of the FGS Failure Conditions and their associated classifications will frequently depend on the phase of flight, aeroplane configuration and the type of operation being conducted. The effect of any control system variability (e.g., tolerances and rigging) on Failure Condition should be considered. The severity of the Failure Conditions can also be mitigated by various design strategies (see Section 13.3).

Appendix A presents some considerations for use when assessing the type and severity of condition that results from functional failures. The classifications of Failure Conditions that have been identified on previous aeroplane certification programs are identified. The classifications of Failure Conditions should be agreed with the authority during the CS 25.1309 safety assessment process.

With exception of the Catastrophic failure condition, the classification of failure conditions leading to the imposition of airframe loads should be assessed in accordance with CS 25.302. This requires that the structure be able to tolerate the limit load multiplied by a factor of safety associated with the probability of occurrence of the failure mode. The assessment needs to take into account loads occurring during the active malfunction, recovery or continuation of the flight with the system in the failed state.

Complex integrated systems may require that the total effect resulting from single failure be assessed. For example, some failures may result in a number of Failure Conditions occur which, if assessed individually may be considered a Major effects, but when considered in combination may be Hazardous. Special consideration concerning complex integration of systems can be found in Section 12, Flight Guidance System Integration.

13.3 Failure Condition – Mitigation

The propagation of potential Failure Conditions to their full effect may be nullified or mitigated by a number of methods. These methods could include, but are not limited to, the following:

— failure detection and monitoring,

— fault isolation and reconfiguration,

— redundancy,

— authority limiting, and

— flight crew action to intervene.

Means to assure continued performance of any system design mitigation methods should be identified. The mitigation methods should be described in the Safety Analysis/Assessment document or be available by reference to another document (e.g., a System Description document).

The design of typical FGS allows for the de-selection of control and guidance elements. The long-term effects on occupants and any structural implication of oscillatory failures can be mitigated by de-selection.

13.4 Validation of Failure Conditions

The method of validating of Failure Conditions will depend on the effect of the condition, assumptions made and any associated risk. The severity of some Failure Conditions may be obvious and other conditions may be somewhat subjective. If flight crew action is used to mitigate the propagation of the effect of a Failure Condition, the information available to the flight crew to initiate appropriate action (e.g., motion, alerts, and displays) and the assumed flight crew response should be identified. It is recommended that there be early coordination with the regulatory authority to identify any program necessary to validate any of these assumptions.

The validation options for Failure Conditions include:

— Analysis

— Laboratory Testing

— Simulation

— Flight Test

It is anticipated that the majority of Failure Condition can be validated by analysis to support the probability aspect of the CS 25.1309 assessment. The analysis should take account of architectural strategies (e.g., redundant channels, high integrity components, rate limit/magnitude limiting, etc.).

It may be necessary to substantiate the severity of a Failure Condition effect by ground simulation or flight test. This is particularly true where pilot recognition of the failure condition requires justification or if there is some variability in the response of the aeroplane. Failure Conditions that are projected to be less probable than 10^{-7} per flight hour, independent of effect severity, need not be demonstrated in flight-test.

Section 14 – Compliance Demonstration using Flight Test and Simulation - provides guidance on the assessment of 'traditional' Failure Conditions. New and novel functionality may require additional assessment methods to be agreed with the authority.

13.5 Specific Considerations

The following paragraphs identify specific considerations that should be given to potential Failure Conditions for various phases of flight.

13.5.1FGS Function during Ground Operations

The potential hazard that may result due to inappropriate autopilot, autothrust or other system control action during maintenance operations, while the aeroplane is parked at the gate or during taxi operations should be assessed. System interlocks or crew or maintenance procedures and placards may mitigate these hazards.

13.5.2 FGS Operations in close proximity to the ground

The response of the aeroplane to failures in an automatic flight control system could have implications on the safety of operations when the aeroplane is close to the ground. For the purpose of this advisory circular, close to the ground can be assumed to be less than 150 m (500 ft) above the lift-off point or touchdown zone or a runway. A specific safety assessment is required if approval is sought for automatic flight control operation where the autopilot is engaged, or remains engaged in close proximity to the ground.

NOTE: Operation in low visibility conditions requires additional consideration and CS AWO Subparts should be used for those additional considerations.

13.5.2.1 Takeoff

If approval is sought for engagement of the autopilot below 150 m (500 ft) after lift-off, an assessment of the effect of any significant FGS failure conditions on the net vertical flight path, the speed control and the bank angle of the aeroplane should be conducted. An Autopilot Minimum Engage Altitude after Takeoff will be established based, in part, on the characteristics of the aeroplane in response to the failures and the acceptability of flight crew recognition of the condition.

A pilot assessment of certain Failure Conditions may be required (see Section 14 – Compliance Demonstration using Flight Test and Simulation). The minimum engagement altitude/height after takeoff based upon the assessment should be provided in the AFM.

13.5.2.1.1 Vertical Axis Assessment

The operational objective during the initial climb is to maintain an appropriate climb profile to assure obstacle clearance and to maintain an appropriate speed profile during climbout (refer to Section 11, Characteristics of Specific Modes).

FGS Failure Conditions should be assessed for the potential for:

— a significant reduction in the net takeoff flight path below 150 m (500 ft),

— a significant increase in pitch attitude that results in the aeroplane speed dropping to unacceptable values.

Failures Conditions with a probability greater than 1×10^{-7} per flight hour that have an effect requiring the pilot to intervene should be evaluated for a potential AFM limitations or procedures.

13.5.2.1.2 Lateral Axis Assessment

The operational objective during the initial climb is to maintain an appropriate heading or track to provide separation from potential adjacent runway operations.

FGS failure conditions should be assessed for the potential for producing a bank angle that results in significant deviation from the runway track or intended track.

Failures Conditions with a probability greater than 1 x 10^{-7} per flight hour that have an effect requiring pilot action should be evaluated for a potential AFM limitations or procedures.

13.5.2.2 Approach

If the autopilot is to remain engaged below 150 m (500 ft) above the touchdown zone during approach, an assessment of the effect of any significant FGS failure conditions on the net vertical flight path, the speed control and the bank angle of the aeroplane should be conducted. The lowest point on the approach appropriate for the use of the autopilot will be established based on the characteristics of the aeroplane in response to the failure conditions and the acceptability of flight crew recognition of the condition.

A number of approach operations may be conducted using automatic flight control. These can include, but not be limited to, the following:

— ILS, MLS, GLS,

— RNAV (e.g., LNAV and VNAV),

— NAV (e.g., VOR, LOC, Backcourse),

— Open loop flight path management (e.g., Vertical Speed, Flight Path Angle, Track or Heading Select).

Some operations may be conducted with a single autopilot channel engaged and some operations may be conducted with multiple autopilots engaged. The engagement of multiple autopilots may have the effect of mitigating the effect of certain failure conditions. The effectiveness of these mitigation methods should be established.

The type of operation and the prevailing visibility conditions will determine the decision altitude/decision height (DA(H)), or minimum descent altitude or height (MDA(H)), for a particular flight operation. The operation may continue using automatic flight control if the visual requirements are met.

The lowest altitude at which the autopilot should remain engaged could vary with the type of operation being conducted. The resultant flight path deviation from any significant failure condition would impact the autopilot minimum operational use height.

Assessment of certain failure conditions may be required (see Section 14 – Compliance Demonstration using Flight Test and Simulation). The minimum use height for approach should be provided in the AFM.

13.5.2.2.1 Vertical Axis Assessment

The operational objective during the approach is to maintain an appropriate descent profile to assure obstacle clearance and to maintain an appropriate speed profile.

FGS Failure Conditions should be assessed for the potential for:

— a significant reduction in the approach flight path when below 150 m (500 ft) above touchdown,

— a significant increase in pitch attitude that results in the aeroplane speed dropping to unacceptable values.

Failures Conditions with a probability greater than 1 x 10^{-7} per flight hour that have an effect requiring pilot action should be evaluated for potential AFM limitations or procedures.

13.5.2.2.2 Lateral Axis Assessment

The operational objective during the approach is to maintain an appropriate track to provide alignment with the runway centreline, or intended flight path, to support the landing.

FGS Failure Conditions should be assessed for the potential for producing a bank angle that results in significant deviation from the runway track or intended track.

Failures with a probability greater than 1 x 10^{-7} per flight hour that have an effect requiring pilot action should be evaluated for appropriate AFM limitations or procedures.

13.5.3 Cruise Operations

The primary concern during cruise operations is the effect the aeroplane response to Failure Conditions may have on the occupants. At a minimum, the accelerations and attitude resulting from any condition should be assessed. The mitigation of the effect of a Failure Condition by the flight crew may not be as immediate as during takeoff and landing operations. Section 14 provides guidance and considerations for this phase of flight.

13.5.4 Asymmetric Thrust during Autothrust Operation

During autothrust operation, it is possible that a failure (e.g., engine failure, throttle lever jam, or thrust control cable jam) could result in significant asymmetric thrust failure condition that may be aggravated by the continued use of the autothrust system. Because the FGS could potentially compensate for the asymmetric condition with roll (and possibly yaw) control, the pilot may not immediately be aware of the developing situation. Therefore, an alert should be considered as a means of mitigation to draw the pilot's attention to an asymmetric thrust condition during FGS operation.

13.6 Failure to Disengage the FGS

The requirement for quick disengagement for the autopilot and autothrust functions is intended to provide a routine and intuitive means for the flight crew to quickly disengage those functions. The implication of failures that preclude the quick disengagement from functioning should be assessed consistent with the guidelines of AMC 25.1309.

The CS 25.1309 assessment should consider the effects of failure to disengage the autopilot and/or autothrust functions during the approach using the quick disengagement controls. The feasibility of the use of the alternative means of disengagement defined in Section 8.1.2.3 should be assessed.

If the assessment asserts that the aircraft can be landed manually with the autopilot and/or autothrust engaged, this should be demonstrated in Flight Test.

14 COMPLIANCE DEMONSTRATION USING FLIGHT TEST AND SIMULATION

The validation of the performance and integrity aspects FGS operation will typically be accomplished by a combination of the following methods:

— Analysis

— Laboratory Test

— Simulation

— Flight Test

The criteria to be used for establishing compliance with CS 25.1301, 25.1309 and 25.1329 may be found in Sections 8, 9, 10, 11, 12, and 13 of this document. The type and extent of the various validation methods may vary dependent upon the FGS functionality, certification considerations, the applicant's facilities, and various practicality and economic constraints.

This section focuses on compliance demonstration by flight test or simulation with flight crew participation. The section includes the evaluation necessary to confirm acceptable performance of intended functions, including the human-machine interface, and the acceptability of failure scenarios. The specific requirements for flight or simulator evaluation will consider the specifics of the applicant's design, the supporting engineering analysis and the scope and depth of the applicants laboratory testing.

The certification flight test program should investigate representative phases of flight and aircraft configurations used by the FGS. The program should evaluate all of the FGS modes throughout appropriate manoeuvres and representative environmental conditions, including turbulence. Combinations of FGS elements (e.g., autopilot engaged and autothrust disengaged) should be considered. Certain failure scenarios may require flight or simulator demonstration. The aeroplane should contain sufficient instrumentation such that the parameters appropriate to the test are recorded (e.g. normal acceleration, airspeed, height, pitch and roll angles, autopilot engagement state). The flight test instrumentation should not affect the behaviour of the autopilot or any other system.

Figure 14-1 depicts the relationship between this section and the rest of the document.

An important part of the pilot in the loop evaluation is validation of human factors. A thorough evaluation of the human-machine interface is required to ensure safe, effective, and consistent FGS operation. Portions of this evaluation will be conducted during flight test. Representative simulators can be used to accomplish the evaluation of human factors and workload studies. The level and fidelity of the simulator used should be commensurate with the certification credit being sought and its use should be agreed with the regulatory authority.

If the FGS includes takeoff and/or approach modes, the criteria in CS-AWO Subparts 1, 2, 3 and 4 should be considered for applicability in developing the overall and integrated flight test and simulation requirements. AMC No.2 to CS 25.1329 contains procedures that may be used to show compliance.