MASSACHUSETTS INSTITUTE OF TECHNOLOGY

APOLLO

GUIDANCE, NAVIGATION AND CONTROL

Approved: E M Copps Date: 2 Jan
E. COPPS, DIRECTOR, SYSTEMS ENGINEERING
APOLLO GUIDANCE AND NAVIGATION PROGRAM

Approved: Fred H. Martin Date: 1/3/69
F. H. MARTIN, COLOSSUS PROJECT MANAGER
APOLLO GUIDANCE AND NAVIGATION PROGRAM

Approved: R. H. Battin Date: 3 Jan 69
R. H. BATTIN, DIRECTOR, MISSION DEVELOPMENT
APOLLO GUIDANCE AND NAVIGATION PROGRAM

Approved: D. G. Hoag Date: 3 Jan 69
D. G. HOAG, DIRECTOR
APOLLO GUIDANCE AND NAVIGATION PROGRAM

Approved: Ralph R. Ragan Date: 3 Jan 69
R. R. RAGAN, DEPUTY DIRECTOR
INSTRUMENTATION LABORATORY

R-577

GUIDANCE SYSTEM OPERATIONS PLAN FOR MANNED CM EARTH ORBITAL AND LUNAR MISSIONS USING PROGRAM COLOSSUS I (REV. 237) AND PROGRAM COLOSSUS IA (REV. 249) SECTION 2 DATA LINKS (Rev. 2)

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MIT INSTRUMENTATION LABORATORY
CAMBRIDGE 39, MASSACHUSETTS

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R-577

GUIDANCE SYSTEM OPERATIONS PLAN FOR MANNED CM EARTH ORBITAL OR LUNAR MISSIONS USING PROGRAM COLOSSUS

SECTION 2 DATA LINKS

Signatures appearing on this page designate approval of this document by NASA/MSC.

Approved: _____ Date: 7/21/69
Thomas F. Gibson
Asst. Chief, Flight Software Branch
Manned Spacecraft Center, NASA

Approved: _____ Date: 7/21/69
James C. Stokes, Jr.
Chief, Flight Software Branch
Manned Spacecraft Center, NASA

Approved: _____ Date: 7-30-69
Lynwood C. Dunseith
Chief, Flight Support Division
Manned Spacecraft Center, NASA

Date: 10 June 1968

REVISION INDEX COVER SHEET

GUIDANCE SYSTEM OPERATIONS PLAN

GSOP # R-577 Title: For Manned CM Earth Orbital and Lunar Missions Using Program COLOSSUS

Section #2 Title: Data Links (Revision 1)

This publication, a complete new revision (Rev. 1), incorporates revisions and additions as indicated below:

Revision 1

PCR-(PCN)	Description of Change
PCR-154	Update GSOP, Section 2, for typing errors, scaling changes, extra detail and description.
PCR-157	Lambert target updates conform to verb 71 format.
PCR-172(MIT-101)*	Change word-order of Entry/Update list.
PCR-174(MIT-108)*	LANDMARK I.D. added to P22 downlist.
PCR-422(MIT-146)*	Words 20 and 33 of the Entry/Update list were interchanged. Word 100 of the same list is now GAMMA (EI) and Range for Initialization.
PCN-417*	Use of ENDSAFE terminated.

Because of the numerous changes required by PCR #154 in Revision 1, there will be no PCR/PCN reference information at the bottom of any page which changed as a result of PCR #154 only.

Additional UPLINK information resulted in the following new sections:

2.1.5	Use of the Contiguous Block Update Verb.
2.1.5.1	CMC CSM/LM State Vector Update.
2.1.5.2	CMC Desired REFSMMAT Update.
2.1.5.3	CMC External DELTA V Update.
2.1.5.4	CMC Retrofire External DELTA V Update.
2.1.5.5	CMC Entry Update.
2.1.5.6	CMC Lambert Target Update.
2.1.5.7	CMC Lambert Return to Earth Update.

*Indicates an MIT Program Change Notice (PCN)

Date: November 1968

REVISION INDEX COVER SHEET

GUIDANCE SYSTEM OPERATIONS PLAN

GSOP # R-577 Title: For Manned CM Earth Orbital and Lunar Missions Using Program COLOSSUS 1 (Rev 237)

Section # 2 Title: Data Links (Revision 2)

This publication, a complete new revision (Rev 2), is expanded in many places over the previous one (Rev 1, dated June 1968). Only changes in specifications, resulting from the PCR/PCN information listed below, will be indicated by a solid-black line at the edge of the page along with the appropriate reference number at the bottom of the page. Any editorial changes will be marked by a vertical series of black dots at the page's edge.

PCR/PCN	Description of Change
PCR 439.1*	Deleted logic in P52 to check status of preferred orientation flag. It is not required now in the Preferred REFSMMAT Update.
PCR 237	Update GSOP, Section 2 Rev 1, for typing errors, scaling changes additions and revisions.
PCN 585*	Scaling in word 27b (Rend/Pre) should be changed to, "multiply by 18.52".
	FAILREG +2 may also contain a first digit of 1 or 5.
	Delete word "RESTART", IMODES 30, bit 7.

* Indicates an MIT Program Change Notice (PCN).

Guidance System Operations Plan For Manned
CM Earth Orbital and Lunar Missions Using
Program COLOSSUS 1 (Rev 237)

Section 2 Data Links (Revision 2)

Table of Contents

2. GNCS Data Links (Preface)

The Guidance System Operations Plan is published as seven separate volumes (sections) as follows:

Section 1	Pre-Launch
Section 2	Data Links
Section 3	Digital Autopilots
Section 4	Operational Modes
Section 5	Guidance Equations
Section 6	Control Data
Section 7	Error Analyses

This volume, Section 2 of the Guidance System Operations Plan for Manned CM Earth Orbital and Lunar Missions using Program COLOSSUS, 1 (Rev 237), describes the GNCS Data Links: Digital Uplink to CMC (P27), CM Digital Downlink for use on these missions.

This volume constitutes a control document to govern the structure of Uplink and Downlink Programs in COLOSSUS. Revisions to this plan which reflect changes in the above control items require approval from NASA.

The material of Section 2 of this GSOP is arranged:

2.1	Digital Uplink to CMC (P27)
2.2	CMC Digital Downlink

2.1 Digital Uplink to CMC (P27)

By means of the CMC UPLINK, ground control can insert data or issue instructions to the CMC in the same manner that these functions are normally performed by the spacecraft crew in using the DSKY keyboard. The CMC is programmed to accept the following UPLINK inputs:

1. LIFTOFF TIME INCREMENT: Provides ground capability to increment or decrement the CMC clock, LM and CSM state vector times and TEPHEM (time) with a double precision octal time value, scaled centiseconds/2^{28}.

2. CONTIGUOUS BLOCK UPDATE: Provides ground capability to update, within certain bounds, from 1 to 18 consecutive E memory registers in the same EBANK.

3. SCATTER UPDATE: Provides ground capability to update from 1 to 9 non-consecutive E memory registers in the same or different EBANKs.

4. OCTAL CLOCK INCREMENT: Provides ground capability to increment or decrement the CMC clock with a double precision octal time value scaled centiseconds/2^{28}.

All information received by the CMC from the uplink is in the form of keyboard characters. Each character is assigned an identifying code number called its character code. Each character code transmitted to the CMC is sent as a triply redundant uplink word preceded by a leading "1" bit. Thus, if C is the 5-bit character code, then the 16 bit uplink word has the form:

$$1\ C\ \overline{C}\ C$$

where $\overline{C}$ denotes the bit-by-bit complement of C. (Table 2-1 defines all the legal input keycodes.) To these 16 bits of information the ground adds a 3-bit code specifying the system aboard the spacecraft which is to be the final recipient of the data and a 3-bit code indicating the spacecraft which should receive the information. The 22 total bits are sub-bit encoded (replacing each bit with a 5-bit code for transmission). If the message is received and successfully decoded, the on-board receiver will send back an 8-bit "message accepted pulse" to the ground and shift the original 16 bits of the uplink word to the CMC (1 C $\overline{C}$ C). The leading "1" bit causes an interrupt within the CMC after all 16 bits have been shifted from the uplink receiver.

Any ground command sequence normally transmitted via the uplink may be duplicated by the astronaut via the keyboard. All reference to uplink words used in

TABLE 2-1

Character	Uplink Word
0	1 10000 01111 10000
1	1 00001 11110 00001
2	1 00010 11101 00010
3	1 00011 11100 00011
4	1 00100 11011 00100
5	1 00101 11010 00101
6	1 00110 11001 00110
7	1 00111 11000 00111
8	1 01000 10111 01000
9	1 01001 10110 01001
VERB	1 10001 01110 10001
NOUN	1 11111 00000 11111
ENTER	1 11100 00011 11100
ERROR RESET	1 10010 01101 10010
CLEAR	1 11110 00001 11110
KEY RELEASE	1 11001 00110 11001
+	1 11010 00101 11010
-	1 11011 00100 11011

NOTE: It is good operational procedure to end every uplink message with a KEY RELEASE.

this section are in the form transmitted from the uplink receiver to the CMC. Therefore, they do not contain the vehicle or subsystem addresses added by the ground facilities.

During update program (P27) execution, the following registers may be monitored via the P27 Downlink List:

1. UPBUFF - Contains all input data, including index value, ECADR value(s) and update parameters. There are 20 (decimal) UPBUFF registers numbered sequentially from UPBUFF + 0 to UPBUFF + 19D where the D indicates decimal notation.

2. UPVERB - Contains second digit of update verb being used, e.g., "0" for Verb 70, "1" for Verb 71, etc.

3. UPOLDMOD - Contains value of program interrupted by P27, e.g., 00 and 02 for programs 00 and 02 ; program 27 is inhibited from interrupting any other programs. *

4. COMPNUMB - Contains value of number of components to be processed by P27. Once set, it remains fixed during complete update operation.

5. UPCOUNT - Used for indexing UPBUFF. The contents of this register may vary from one (1) to the value contained in COMPNUMB. This register always contains the octal identifier of the parameter that is being loaded.

If the CMC received an improperly coded word from the uplink receiver during the load (i.e., not "1 CC̄C") it sets BIT 4 of FLAGWRD7 to "one", which is transmitted via Downlink to the ground station. When this occurs, the ground station should correct the transmission by sending the following uplink word:

1 00000 00000 00000

(which clears the INLINK register) and follow this by transmitting "ERROR RESET" (which will set BIT 4 of FLAGWRD7 to zero).** If "CLEAR" is transmitted immediately following "ERROR RESET", the ground station then may begin the corrected transmission with the first word of the 5 octal digits that was being sent when the alarm condition occurred. The "CLEAR" button is used after the "ERROR RESET" to blank the data display register (R1). The ground station should then continue the update by using UPCOUNT to indicate the specific parameter being processed and resume the update function by re-transmitting the parameter beginning with the first octal character.

---

* It is possible to update when program lights are blanked by a FRESH START (MODREG is 77777_8).

** "ERROR RESET" must be sent via uplink to set BIT4 of FLAGWRD7 to zero. DSKY "ERROR RESET" does no affect this bit.

If the ground wishes to continue loading without transmitting the "CLEAR" code it must determine which character was in error when failure occurred, and resume uplink transmission from the point of failure. This may be determined by monitoring the display in R1 as well as the contents of UPCOUNT.

This program may be entered only from P00, or P02 for the CM. If the CMC is not in one of the programs indicated above when any update VERB is sent uplink, the "Operator Error" lamp will be illuminated, the uplink activity light will be turned "OFF" and the computer will ignore the request, via the specified update VERB, to transfer control to P27.

2.1.1 CM LIFTOFF TIME INCREMENT

To initiate a double precision LIFTOFF octal time increment the ground station transmitts "VERB70ENTER".

2.1.1.1 Program 27 Verification

The ground station should then await confirmation via Downlink that the CMC is in Program 27.

If P27 is entered, the CMC puts the old program number in UPOLDMOD, sets UPCOUNT to "one", selects the P27 Downlink List for Downlink transmission and flashes V21N01 which requests a data load for UPBUFF + 0.

If P27 is entered for a Verb 70 update, 0 is placed in UPVERB and 2 is placed in COMPNUMB. Following P27 verification and confirmation of UPVERB and COMPNUMB sent via Downlink, the ground station should transmit the double precision octal time XXXXX ENTER XXXXX ENTER, where time is in centiseconds scaled at 2^{28}. A negative time value (decrement) should be transmitted in one's complement form. It should be noted that UPCOUNT is incremented by 1 after the ENTER following the most significant part of the double precision time. P27 uses the contents of UPCOUNT to calculate the next UPBUFF location for the V21N01.

2.1.1.2 Data Verification and Termination

After the final ENTER associated with the last update has been transmitted, P27 flashes V21N02 which is a request to the ground station to verify all the update data and to perform one of the following functions:

1. Accept all the update data entered
2. Modify some or all of the update data
3. Reject all of the update data

2.1.1.2.1 Accept All the Update Data Entered

If the ground station verifies that the content of the UPBUFF register is correct, it should transmit "VERB33ENTER" to signal P27 to process the update data. For the Verb 70 update, P27 inverts BIT 3 of FLAGWRD7 and determines if the State Vector data is being used by the orbital integration routine. If so, further P27 instruction executions are delayed (P27 dormant) until the integration routine is complete. A display of "27" in the program lights, along with a ground verification that BIT3 of FLAGWRD7 has been inverted and that the operator error light is "OFF", should indicate to the operator that the completion of P27 is temporarily being delayed.

After P27 is re-activated or if it initially finds that the integration routine is not in use, it will inhibit other routines from using State Vector data and complete the data verification requirements for the specific update Verb in use. (For each Verb, see appropriate verification section.)

2.1.1.2.1.1 Verb 70 Double Precision Time Verification

Program 27 verifies that the double precision octal time can be subtracted from the CMC clock without causing overflow. (For this operation two of the UPBUFF registers, UPBUFF + 18D and 19D, are used as temporary buffers for TIME2 and TIME1.) If the double precision input time can be subtracted from the CMC clock without causing overflow, P27 proceeds to increment TEPHEM and decrement the CMC clock, the CSM State Vector time, and the LM State Vector time. Program 27 will then turn the uplink activity light "OFF", replace the downlink list code in DNLSTADR with the code for the previous program, release the State Vector data for other routines, and reinstate the previous program.

If, on the other hand, an overflow would occur, P27 will leave the CMC clock intact and turn the operator error light "ON". It will then turn the uplink activity light "OFF", replace the downlink list code in DNLSTADR with the code for the previous program, release the State Vector data, and reinstate the previous program.

2.1.1.2.2 Modify Some or All of the Update Data

If during the verification time some of the UPBUFF registers are found to be in error, the ground station may make corrections by either of the following methods:

a. Individual parameters in UPBUFF + 0 to UPBUFF + 19D may be

changed by sending a two digit octal identifier followed by the ENTER code. For example, if input word 2 (UPBUFF+1) required change, the ground station would transmit "02ENTER". This causes P27 to display the UPBUFF+1 address in R3 and flash V21N01, requesting a new octal data load from the ground. After transmission of the data and its ENTER code, P27 repeats the V21N02 flash to request data acceptance, modification or rejection (section 2.1.1.2). NOTE: If the octal identifier is ≤ 0 or $>$ COMPNUMB, P27 will continue the V21N02 flash and completely disregard the value just entered. It should also be noted that the contents of UPCOUNT is never changed during line by line correction.

b. If several parameters are to be modified, the ground station may change each separately as in step "a" above, or it may choose to terminate and re-initiate the load. To terminate the load the ground must transmit "VERB34ENTER" which will cause the CMC to return to the program it was in before the update was initiated. (P27 turns the uplink activity light "OFF", and switches to the previous Downlink list before returning control to the other program.)

To resume its update the ground station would re-transmit the update VERB followed by the complete update load.

2.1.1.2.3. Reject All the Update Data

Update data may be rejected at any time by terminating a load. This is accomplished with the VERB34ENTER sequence described in part "b" of section 2.1.1.2.2 above (first paragraph).

2.1.1.2.4 Effects and Use of "VERB33ENTER"

1. During data loads and prior to the V21N02 flash, transmission of VERB33ENTER will be ignored by P27.

2. During V21N02 flashing, transmission of VERB33ENTER will initiate the procedure described in section 2.1.1.2.1.

3. If line by line correction is initiated (section 2.1.1.2.2), transmission of VERB33ENTER after the octal identifier has been entered will be ignored by P27.

2.1.2 CM Continguous Block Update

To initiate a contiguous E-memory update the ground station should transmit "VERB71ENTER".

Before sending the update data the ground station should perform Program 27 verification as defined in the first three paragraphs of section 2.1.1.1. If P27 is entered, 1 is placed in UPVERB and in UPCOUNT.

The verb 71 data format is defined in section 2.1.2.1 below and the data load requirements are described in section 2.1.2.2.

2.1.2.1 VERB71 Data Entry Format

The VERB71 update data format is as follows (all Es represent ENTERs):

```
I  I  E
A  A  A  A  E
X  X  X  X  X  E
X  X  X  X  X  E
      .
      .
      .
X  X  X  X  X  E
```

where:

1. $3 \leq II \leq 24$ octal. This is the index value used by P27 to process the update data. The index value represents the total number of numeric quantities to be loaded, including the index value itself, the starting address (ECADR) and the update parameters(s). The minimum value of 3 is for a single update parameter load. A maximum value of 24 octal is allowed since the UPBUFF capacity is a 20 (decimal) register buffer for P27. This value represents a maximum of 18 update parameters in addition to the index count and the starting E memory address.

2. AAAA is the first E memory address (ECADR) of the update block to be processed. Bits 1-8 indicate the relative address ($0\text{-}377_8$) within the selected EBANK and bits 9-11 identify the desired EBANK (0-7). Also, for one data load operation, all update parameters must ultimately be stored in the same EBANK. Therefore, the starting address and the length of the block must be chosen so that the complete load is contained in the same EBANK; i.e., (bits 8 - 1 of AAAA) + II-3 must be $\leq$ 377 octal.

3. X X X X X is octal data which is to be loaded. This data is stored in sequential order in UPBUFF+2 and following, up to UPBUFF+19D. Scaling of the data must be the same as that of the internal CMC registers.

2.1.2.2 Data Load Requirements by Ground Station

Following Program 27 verification (V21N01 flashes with the UPBUFF+0 address displayed in R3) the ground station should enter the update data in the manner described below.

2.1.2.2.1 Index Value

The index value I I should be entered as an octal number and visually verified (displayed in R1) prior to transmitting the ENTER code. This value should be within the specified limits (see part 1 section 2.1.2.1 for format).

If an index value < 3 or > 24 octal is erroneously keyed-in followed by the ENTER code, P27 will reject the value and will continue to flash V21N01 until the ground station enters an index value within the specified limits. (Entry of a legal value is indicated when the UPBUFF+0 address value is displayed in R3 and UPCOUNT contains a 2).

If a legal index value is keyed-in but is found to be in error (displayed in R1) before the ENTER code is transmitted, the operator may correct his error by depressing the "CLEAR" key and re-transmitting the new index value followed by the ENTER code. A legally entered value is stored in UPBUFF+0 and COMPNUMB. UPCOUNT is incremented by 1, the next UPBUFF location is computed and V21N01 continues to flash indicating a request for an ECADR load.

If, however, the ground station operator loads a legal index value followed by the ENTER code and then discovers the numeric value to be incorrect (UPBUFF+0 display), then the only means of recovery is to terminate the load (VERB34ENTER) and re-initiate the update VERB. This procedure is necessary since invalid index values cannot be changed if entered in COMPNUMB and will therefore result in an incorrect update if it is not immediately modified.

2.1.2.2.2 E Memory Address Value

The second octal data word to be entered must be the first E memory address (ECADR) of the update data block.

The ENTER code following the ECADR causes P27 to store this value in UPBUFF+1, increment UPCOUNT by 1, compute the next UPBUFF location and continue the V21N01 flash which requests an update data load.

2.1.2.2.3 Update Data

The update parameters which will be stored in sequential E memory locations beginning with a legitimate E memory address (ECADR), as defined in part 2 of section 2.1.2.1, may be loaded in two separate ways.

1. Each octal value may be individually entered and visually verified (address of data is displayed in R3 and data is displayed in R1) prior to transmitting the ENTER code.

   If data is in error the operator may depress the "CLEAR" key and retransmit the correct octal value followed by the ENTER code. This code causes P27 to store the data in the UPBUFF address specified in R3. If more data follows, UPCOUNT is incremented by 1, the next UPBUFF location is computed and V21N01 continues to flash.

   This method of input allows the ground station to make immediate corrections if data errors are detected and to visually verify that each data word is loaded into its specified E memory location.

2. The second method of input is to transmit all the octal update data as quickly as possible and then perform a visual verification of all the data in the UPBUFF registers as specified in section 2.1.1.2.

2.1.2.3 VERB71 Contiguous Block Update Verification

The last ENTER of the update sequence causes P27 to flash V21N02. This is a request to the ground station to accept, modify or completely reject the data load as specified in 2.1.1.2 sections.

VERB33ENTER also causes P27 to check the validity of the ECADR value stored in UPBUFF+1 (this value must meet the requirements specified in part 2 of section 2.1.2.1). If the ECADR value is illegal, P27 rejects all input data, replaces Program 27 with the previous program value, turns the uplink activity light "OFF", turns the operator error light "ON" and switches to the Downlink list for the previous program.

A valid ECADR causes P27 to transfer all the update data from the UPBUFF registers into the specified E memory registers, replace program 27 with the previous program value, turn the uplink activity light "OFF", switch to the Downlink list for the previous program and release the State Vector data.

2.1.3 CM Scatter Update

To initiate an E memory update in non-contiguous E memory locations the ground station should transmit "VERB72ENTER".

Before sending the update data the ground station should perform Program 27 verification as defined in the first three paragraphs of section 2.1.1.1.

If P27 is entered for a VERB72 update, a 2 is placed in UPVERB and a 1 in UPCOUNT. Following P27 verification the ground station performs this update exactly as described for the VERB71 updates. The differences in these two update verbs are noted in the following section.

2.1.3.1 VERB72 Data Entry Format

The VERB72 update format is defined as follows:

```
I I  E
A A A A E
X X X X X E
A A A A E
X X X X X E
.
.
.
A A A A E
X X X X X E
```

where:

1. $3 \leq I I \leq 24$ octal. The difference between this index value and the VERB71 index value is that this value must always be odd. This is due to the fact that each update parameter must have its specified E memory address. Thus, the index count includes itself and up to 9 pairs of update words. An even number index value, although accepted at this point in the procedure, will cause rejection of VERB72 data as indicated in section 2.1.3.3. Additionally, Program 27 is replaced with the previous program value, the uplink activity light is turned "OFF", the operator error light is turned "ON", the State Vector data is released and the Downlink list is switched for use by the previous program.

2. All A A A As represent the ECADRs. (Each A A A A is the ECADR of the register to be loaded with the X X X X X immediately following.) Note that update data entered via VERB72 may be loaded into different EBANKs.

3. All X X X X Xs are in octal and scaled the same as the internal CMC registers.

2.1.3.2 Data Load Requirements by Ground Station

The load requirements of VERB72 are identical to VERB71 (see sections 2.1.2.2 and 2.1.2.2.1 through 2.1.2.2.3).

2.1.3.3 VERB72 Scatter Update Verification

The last ENTER of the update sequence will cause P27 to flash V21N02. This is a request to the ground to accept, modify or completely reject the data load as specified in 2.1.1.2 sections.

VERB33ENTER also causes P27 to check the COMPNUMB value and determine if each ECADR value is legal (see section 2.1.2.1 part 2). If COMPNUMB is even or if any ECADR value is illegal P27 will perform exactly as specified in the second paragraph of section 2.1.2.3.

If, however, COMPNUMB and all ECADRs are valid P27 will perform exactly as specified in the third paragraph of section 2.1.2.3.

2.1.4 CMC Octal Clock Increment

To initiate a double precision octal time increment the ground station transmits "VERB73ENTER".

The loading procedure for this update is identical to the VERB70 update defined in section 2.1.1 except that 3 is placed in UPVERB instead of 0.

If the update is acceptable, it is immediately used to increment the clock (i.e., positive double precision time is added to the clock). No delay is encountered if the orbital integration routine is in use since the CSM and LM state vector time registers and the TEPHEM register are not modified.

2.1.5 Use of the Contiguous Block Update VERB

VERB 71, defined in section 2.1.2, can be used to perform the following updates:

1. CMC CSM/LM STATE VECTOR UPDATE
2. CMC DESIRED REFSMMAT UPDATE
3. CMC REFSMMAT UPDATE
4. CMC EXTERNAL DELTA V UPDATE
5. CMC RETROFIRE EXTERNAL DELTA V UPDATE
6. CMC ENTRY UPDATE
7. CMC LAMBERT TARGET UPDATE
8. CMC LANDING SITE VECTOR UPDATE

In defining each of these updates, it is assumed that the ground station has transmitted VERB71 ENTER and performed Program 27 verification as required prior to transmittal of the index value, ECADR and update parameters. It is also assumed that final verification of each update will be done as specified in section 2.1.2.3.

2.1.5.1 CMC CSM/LM STATE VECTOR UPDATE

This data consists of a single precision state vector identifier, three (3) double precision components of position, three (3) double precision components of velocity and a double precision time. The identifier (UPSVFLAG) indicates CSM or LM and whether coordinates are earth-centered or moon-centered as follows:

1 = CSM		2 = CSM	
-1 = LM	earth-centered *	-2 = LM	moon-centered

Note that the CMC, at the next permanent memory state-integration, may change the origin, based upon computed position. The position and velocity components should be in reference coordinates scaled as follows:

	earth-centered	moon-centered
Position	meters/2^{29}	meters/2^{27}
Velocity	(meters/centisecond)/2^{7}	(meters/centisecond)/2^{5}

The time associated with the state vector should be relative to CMC clock zero. The identifier is scaled units/2^{14}. Time is scaled centiseconds/2^{28}.

The CMC is a fixed point machine with the point just to the left of the most significant bit.

The scaling indicated above will be sufficient to force the 3 components of position and the 3 components of velocity and time to numbers less than one.

To form the double precision quantities ready for coding and transmission, the scaled magnitudes of time and each component of position and velocity should be expressed as two binary words as follows:

---

*If a quantity other than 0, -0, 2 or -2 is loaded into UPSVFLAG, the data will also be interpreted as earth-centered. A 0 or -0 will update the UPSVFLAG erasable but the CMC will not perform a state vector update. In the other numeric cases a valid state vector update will be performed (earth-center).

1st word:

0	X	X	X	X	X	X	X	X	X	X	X	X	X	X
	2^{-1}	2^{-2}	2^{-3}	2^{-4}	2^{-5}	2^{-6}	2^{-7}	2^{-8}	2^{-9}	2^{-10}	2^{-11}	2^{-12}	2^{-13}	2^{-14}

2nd word:

0	X	X	X	X	X	X	X	X	X	X	X	X	X	X
	2^{-15}	2^{-16}	2^{-17}	2^{-18}	2^{-19}	2^{-20}	2^{-21}	2^{-22}	2^{-23}	2^{-24}	2^{-25}	2^{-26}	2^{-27}	2^{-28}

Each X above represents a binary bit of the appropriate magnitude, the place value of which is indicated below the corresponding X. Once the magnitude of the component is accounted for in the above 28 X's, the sign must be considered.

If the component is positive, the words remain as formed; if the component is negative, the "1s complement" of the 2 words is used (all 1's are replaced by 0's and all 0's by 1's.)

The first word is then transformed into a 5 character octal word. The first character is the octal equivalent of the first three bits, the second character is the octal equivalent of the next three bits, etc. This word is referred to as the "most significant part" of data in the text below. Similarly, the second word is transformed into a 5 character octal word which is the "least significant part" of the data. Table 2-1 lists all the uplink characters with their corresponding binary format.

The CMC CSM/LM STATE VECTOR UPDATE data must be sent in the following sequence:

Octal Identifier	Data Value	Data Definition
1	21_8	(index value) ENTER
2	AAAAA	(ECADR - 1501) ENTER
3	XXXXX	(identifier) ENTER
4	XXXXX	(most sig. part of X position) ENTER
5	XXXXX	(least sig. part of X position) ENTER
6	XXXXX	(most sig. part of Y position) ENTER
7	XXXXX	(least sig. part of Y position) ENTER
10_8	XXXXX	(most sig. part of Z position) ENTER
11_8	XXXXX	(least sig. part of Z position) ENTER

Octal Identifier	Data Value	Data Definition
12_8	XXXXX	(most sig. part of X velocity) ENTER
13_8	XXXXX	(least sig. part of X velocity) ENTER
14_8	XXXXX	(most sig. part of Y velocity) ENTER
15_8	XXXXX	(least sig. part of Y velocity) ENTER
16_8	XXXXX	(most sig. part of Z velocity) ENTER
17_8	XXXXX	(least sig. part of Z velocity) ENTER
20_8	XXXXX	(most sig. part of time from CMC clock zero) ENTER
21_8	XXXXX	(least sig. part of time from CMC clock zero) ENTER

where each "A", "X" and "ENTER" above represent an uplink word.

2.1.5.2 CMC DESIRED REFSMMAT UPDATE

XSMD - XSMD + 17 is a 3 × 3 double precision matrix which represents the Reference to Stable Member Desired Transformation.

The elements of the matrix are scaled, units/2^1.

The following relations must hold:

1. The inner product of any row with itself must equal 0.25
2. The inner product of any column with itself must equal 0.25
3. The inner product of any row with another row must equal 0
4. The inner product of any column with another column must equal 0

The CMC DESIRED REFSMMAT UPDATE must be sent in the following sequence:

Octal Identifier	Data Value	Data Description
1	24_8	(index value) ENTER
2	AAAA	(ECADR - 0306) ENTER
3	XXXXX	(most sig. part of Row 1 Col. 1) ENTER
4	XXXXX	(least sig. part of Row 1 Col. 1) ENTER
5	XXXXX	(most sig. part of Row 1 Col. 2) ENTER
6	XXXXX	(least sig. part of Row 1 Col. 2) ENTER
7	XXXXX	(most sig. part of Row 1 Col. 3) ENTER
10_8	XXXXX	(least sig. part of Row 1 Col. 3) ENTER
11_8	XXXXX	(most sig. part of Row 2 Col. 1) ENTER

[X] Revised [X] Added GSOP # R-577 237 PCR # 439.1 Rev. 2 Date 8/1/68 6/4/68

Octal Identifier	Data Value	Data Description
12_8	XXXXX	(least sig. part of Row 2 Col. 1) ENTER
13_8	XXXXX	(most sig. part of Row 2 Col. 2) ENTER
14_8	XXXXX	(least sig. part of Row 2 Col. 2) ENTER
15_8	XXXXX	(most sig. part of Row 2 Col. 3) ENTER
16_8	XXXXX	(least sig. part of Row 2 Col. 3) ENTER
17_8	XXXXX	(most sig. part of Row 3 Col. 1) ENTER
20_8	XXXXX	(least sig. part of Row 3 Col. 1) ENTER
21_8	XXXXX	(most sig. part of Row 3 Col. 2) ENTER
22_8	XXXXX	(least sig. part of Row 3 Col. 2) ENTER
23_8	XXXXX	(most sig. part of Row 3 Col. 3) ENTER
24_8	XXXXX	(least sig. part of Row 3 Col. 3) ENTER

2.1.5.3 CMC REFSMMAT UPDATE

REFSMMAT - REFSMMAT + 17D is a 3×3 matrix used to convert between reference coordinates and stable member coordinates. The elements of the matrix are scaled, units/2^1.

The CMC REFSMMAT UPDATE must be sent in the following sequence:

Octal Identifier	Data Value	Data Description
1	24_8	(index value) ENTER
2	AAAA	(ECADR - 1735) ENTER
3	XXXXX	(most sig. part of Row 1 Col. 1) ENTER
4	XXXXX	(least sig. part of Row 1 Col. 1) ENTER
5	XXXXX	(most sig. part of Row 1 Col. 2) ENTER
6	XXXXX	(least sig. part of Row 1 Col. 2) ENTER
7	XXXXX	(most sig. part of Row 1 Col. 3) ENTER
10_8	XXXXX	(least sig. part of Row 1 Col. 3) ENTER
11_8	XXXXX	(most sig. part of Row 2 Col. 1) ENTER
12_8	XXXXX	(least sig. part of Row 2 Col. 1) ENTER

Octal Identifier	Data Value	Data Description
13_8	XXXXX	(most sig. part of Row 2 Col. 2) ENTER
14_8	XXXXX	(least sig. part of Row 2 Col. 2) ENTER
15_8	XXXXX	(most sig. part of Row 2 Col. 3) ENTER
16_8	XXXXX	(least sig. part of Row 2 Col. 3) ENTER
17_8	XXXXX	(most sig. part of Row 3 Col. 1) ENTER
20_8	XXXXX	(least sig. part of Row 3 Col. 1) ENTER
21_8	XXXXX	(most sig. part of Row 3 Col. 2) ENTER
22_8	XXXXX	(least sig. part of Row 3 Col. 2) ENTER
23_8	XXXXX	(most sig. part of Row 3 Col. 3) ENTER
24_8	XXXXX	(least sig. part of Row 3 Col. 3) ENTER

2.1.5.4 CMC EXTERNAL DELTA V UPDATE

This data consists of three velocity components in local vertical coordinates, and the time of ignition. The scale factors are

1. $DELVSLV_{x,y,z}$ (meters/centisecond)/2^7
   $DELVSLV_{x,y,z}$ must be in a local vertical system at an origin which corresponds to the CM state (earth-centered or moon-centered) at TIG.
2. TIG centiseconds/2^{28}

The velocity components, sent from the ground must be in the local vertical system defined by the CMC-determined, CSM state vector at TIG-30. In addition, in order for an update to be accepted properly when near the sphere, the CMC must not change the sphere reference between TIG-30 and TIG. (A safe procedure is to not designate TIG within ±3 hours of the sphere crossing.)

The CMC EXTERNAL DELTA V UPDATE data must be sent in the following sequence:

Octal Identifier	Data Value	Data Definition
1	12_8	(index value) ENTER
2	AAAA	(ECADR - 3404) ENTER
3	XXXXX	(most sig. part of $DELVSLV_x$) ENTER
4	XXXXX	(least sig. part of $DELVSLV_x$) ENTER
5	XXXXX	(most sig. part of $DELVSLV_y$) ENTER
6	XXXXX	(least sig. part of $DELVSLV_y$) ENTER
7	XXXXX	(most sig. part of $DELVSLV_z$) ENTER
10_8	XXXXX	(least sig. part of $DELVSLV_z$) ENTER
11_8	XXXXX	(most sig. part of TIG) ENTER
12_8	XXXXX	(least sig. part of TIG) ENTER

2.1.5.5 CMC RETROFIRE EXTERNAL DELTA V UPDATE

This data consists of the latitude and longitude of the entry target, three velocity components in local vertical coordinates and the time of ignition. The scale factors are:

1. GEODETIC LAT(SPL) degrees/360 (North positive)
2. LNG (SPL) degrees/360 (East positive)
3. $DELVSLV_{x,y,z}$ (meters/centisecond)/2^7
4. TIG centiseconds/2^{28}

The CMC RETROFIRE EXTERNAL DELTA V UPDATE date must be sent in the following sequence:

Octal Identifier	Data Value	Data Definition
1	16_8	(index value) ENTER
2	AAAA	(ECADR- 3400) ENTER
3	XXXXX	(most sig. part of LAT (SPL)) ENTER
4	XXXXX	(least sig. part of LAT (SPL)) ENTER
5	XXXXX	(most sig. part of LNG (SPL)) ENTER
6	XXXXX	(least sig. part of LNG (SPL)) ENTER
7	XXXXX	(most sig. part of $DELVSLV_x$) ENTER
10_8	XXXXX	(least sig. part of $DELVSLV_x$) ENTER
11_8	XXXXX	(most sig. part of $DELVSLV_y$) ENTER
12_8	XXXXX	(least sig. part of $DELVSLV_y$) ENTER
13_8	XXXXX	(most sig. part of $DELVSLV_z$) ENTER
14_8	XXXXX	(least sig. part of $DELVSLV_z$) ENTER
15_8	XXXXX	(most sig. part of TIG) ENTER
16_8	XXXXX	(least sig. part of TIG) ENTER

2.1.5.6 CMC ENTRY UPDATE

This data consists of the latitude and longitude of the entry target. The scale factors are:

1. GEODETIC LAT(SPL) degrees/360 (North positive)
2. LNG (SPL) degrees/360 (East positive)

The CMC ENTRY UPDATE data must be sent in the following sequence:

Octal Identifier	Data Value	Data Definition
1	06_8	(index value) ENTER
2	AAAA	(ECADR-3400) ENTER
3	XXXXX	(most sig. part of LAT (SPL)) ENTER
4	XXXXX	(least sig. part of LAT (SPL)) ENTER
5	XXXXX	(most sig. part of LNG (SPL)) ENTER
6	XXXXX	(least sig. part of LNG (SPL)) ENTER

2.1.5.7 CMC LAMBERT TARGET UPDATE

This data consists of: the time of ignition (TIG); the aim point (RTARG) in reference coordinates, which may be earth-centered or moon-centered; the delta time of flight to aim point (DELLT4), and the steering constant (ECSTEER). The target vector sent from the ground must be in the same sphere of influence as the CMC-determined, CSM state vector at TIG-30. In addition, in order for an update to be accepted properly when near the sphere, the CMC must not change the sphere reference between TIG-30 and TIG. (A safe procedure is to not designate TIG within ±2 hours of the sphere crossing.) The scale factors are:

1. TIG — centiseconds/2^{28}
2. $RTARG_{x,y,z}$ — meters/2^{29}
3. DELLT4 — centiseconds/2^{28}
4. ECSTEER — a 14-bit fraction/4

The CMC LAMBERT TARGET UPDATE Data must be sent in the following sequence:

Octal Identifier	Data Value	Data Definition
1	15_8	(index value) ENTER
2	AAAA	(ECADR- 3412) ENTER
3	XXXXX	(most sig. part of TIG) ENTER
4	XXXXX	(least sig. part of TIG) ENTER
5	XXXXX	(most sig. part of $RTARG_x$) ENTER
6	XXXXX	(least sig. part of $RTARG_x$) ENTER
7	XXXXX	(most sig. part of $RTARG_y$) ENTER
10_8	XXXXX	(least sig. part of $RTARG_y$) ENTER
11_8	XXXXX	(most sig. part of $RTARG_z$) ENTER
12_8	XXXXX	(least sig. part of $RTARG_z$) ENTER
13_8	XXXXX	(most sig. part of DELLT4) ENTER
14_8	XXXXX	(least sig. part of DELLT4) ENTER
15_8	XXXXX	(ECSTEER) ENTER

2.1.5.8 CMC Landing Site Vector Update

This data consists of three double-precision position components X, Y, Z, defining the lunar landing site in moon-fixed coordinates, scaled meters/2^{27}.

The CMC LANDING SITE VECTOR UPDATE data must be sent in the following sequence:

Octal Identifier	Data Value	Data Description
1	10_8	(index value) ENTER
2	AAAA	(ECADR-2025) ENTER
3	XXXXX	(most sig. part of RLS X-component) ENTER
4	XXXXX	(least sig. part of RLS X-component) ENTER
5	XXXXX	(most sig. part of RLS Y-component) ENTER
6	XXXXX	(least sig. part of RLS Y-component) ENTER
7	XXXXX	(most sig. part of RLS Z-component) ENTER
10_8	XXXXX	(least sig. part of RLS Z-component) ENTER

2.2 CMC Digital Downlink

The downlink format is controlled by a CMC program. This program is entered on an interrupt caused by an "endpulse" from the telemetry system. The program loads the content of the next two 16-bit CMC registers that are to be transmitted into channels 34 and 35. The loading is accomplished according to the format described in the next paragraph.

Each downlist word consists of 33 significant bits plus seven repetition bits. The first bit is a "word order code bit". The next 16 bits comprise the contents of one 16-bit CMC register (15 bits of data followed by an odd parity bit). The final 16 bits are the content of another 16-bit CMC register. Since the spacecraft downlink is organized in 8-bit segments, seven "filler bits" are transmitted to follow the 33 bits outlined above in order to use all the downlink space available. These filler bits are repetitions of the first seven bits of the first CMC register transmitted.

Thus the form in which the content of the two CMC registers is arranged for transmission as a sequence of 40 CMC downlink bits (represented by X) on channels 34 and 35 may be pictured as shown in the table below:

		Channel 34																
Reg #1	X Word Order Code	X 15_1	X 14_1	X 13_1	X 12_1	X 11_1	X 10_1	X 9_1	X 8_1	X 7_1	X 6_1	X 5_1	X 4_1	X 3_1	X 2_1	X 1_1	X P_1	} word
		Channel 35																
	Reg #2	X 15_2	X 14_2	X 13_2	X 12_2	X 11_2	X 10_2	X 9_2	X 8_2	X 7_2	X 6_2	X 5_2	X 4_2	X 3_2	X 2_2	X 1_2	X P_2	} word
		Channel 34																
	Reg #1	X 15_1	X 14_1	X 13_1	X 12_1	X 11_1	X 10_1	X 9_1										} repeat

Table Showing CMC Downlink Bits

The first word in any list contains the "ID" and synchronization registers and has a word order code bit of zero. (All other downlink words have word order code bits of one except word 51 on the standard downlists which has a word order code bit of zero to indicate the mid-point of the standard downlists.) The ID register marks the beginning of a list and identifies the list being transmitted. The synchronization (sync) register always contains the same sixteen bits (111 111 011 100 000 0), which are used to synchronize remote site downlink processing equipment. The content of the standard lists and the programs in which they are transmitted are described in section 2.2.2.

The standard CMC downlink lists contain 100 downlink words (200 CMC registers). The CMC digital downlink is transmitted at a rate of 50 words per second at

high bit rate and 10 words at low bit rate. Therefore, transmission of the standard list requires two seconds at high bit rate and ten seconds at the low bit rate.

2.2.1 Erasable Memory Dump Downlist

Upon reception of a Verb 74 Enter from the keyboard or the uplink, the computer will interrupt the nominal downlist being transmitted and start transmitting the erasable memory dump downlist. The first word of the erasable memory dump downlist is an ID word, 01777_8 and the same pattern of synch bits as on the standard list. The word order code for this downlink word will be zero. The next 129 downlink words have word order codes of one and make up the remainder of the 130 word dump downlink list. Word 2 of this list (i.e., the word following the ID word) contains a "packed indicator" code in the first register and the contents of TIME1 in the second register. TIME1 is the least significant clock register and is described later in this section under the standard lists. The "packed indicator" identifies which erasable bank and which pass through that bank is contained in the present list as follows:

Bits 15 & 14 - zero

Bits 13 & 12 - 00 for 1st pass
01 for 2nd pass
10 for 3rd pass
11 for 4th pass

Bits 11 thru 9 - gives EBANK number

Bits 8 thru 1 - zeros

The next 128 downlink words (256 registers) are the contents of the erasable bank indicated in the packed indicator.

After transmitting the 130 downlink word list (one ID word, one packed indicator and time word, and 128 data words), the downlink will transmit the ID word again, followed by the packed indicator, followed by the contents of the next erasable bank etc. In this way, one complete pass through erasable memory will require 20.8 seconds. The computer will make 1, 2, or 4 complete passes through the complete erasable memory before returning to the standard downlist. The number of passes made is determined by the contents of an erasable register DUMPCNT as follows:

20000_8 = 4 passes

10000_8 = 2 passes

04000_8 = 1 pass

This erasable register will be loaded during prelaunch in the erasable load with an initial value and may be changed via P27 by the uplink (see sec 2.1) from the ground DSKY or from the spacecraft DSKY.

NOTE: After completion of the erasable dump downlist the interrupted list will be started at the ID word. Since no programs are interrupted during the transmission of the erasable memory downlist, some of the registers transmitted may have different contents on different passes through the erasable.

2.2.2 Standard Downlists

For this mission there are five standard downlists, each associated with a set of programs, as follows:

A. The Powered List is transmitted during

40 SPS Thrust
41 RCS Thrust
47 Thrust Monitor
61 Entry Preparation Program

B. The Coast and Align List is transmitted during

00 CMC Idling
01 Prelaunch Initialization
02 Gyro Compassing
03 Optical Verification of azimuth
06 CMC Power Down
07 System Test
11 Earth Orbit Injection (EOI) Monitor
51 IMU Orientation Determination
52 IMU Realignment Program
53 Backup IMU Orientation Determination
54 Backup IMU Realignment

C. The Rendezvous and Prethrust List is transmitted during

17 CSM TPI Search
20 Rendezvous Navigation
21 Ground Track Determination
23 Cislunar Navigation
30 External ΔV Maneuver Guidance
31 Lambert Aim Point Maneuver Guidance
34 Transfer Phase Initiation (TPI) Guidance
35 Transfer Phase Midcourse (TPM) Guidance
37 Return to Earth Maneuver Guidance
38 Stable Orbit Rendezvous Guidance
39 Stable Orbit Rendezvous Midcourse Guidance
74 LM Transfer Phase Initiation (TPI) Targeting
75 LM Transfer Phase Midcourse (TPM) Targeting
77 LM TPI Search Program
78 LM Stable Orbit Rendezvous
79 LM Stable Orbit Rendezvous Midcourse Targeting

D. The Entry and Update List is transmitted during
   27 CMC Update
   62 CM/SM Separation and Pre-entry Maneuver
   63 Entry Initialization
   64 Post 0.05 G Entry Mode
   65 Up Control Entry Mode
   66 Ballistic Entry Mode
   67 Final Entry Mode

E. The P-22 List is transmitted during
   22 Orbital Navigation

The list switching is accomplished as follows: The DOWNLINK program, at the beginning of a pass, uses the ID word to trigger selection of the appropriate list for that pass. Whenever a new program is entered, it sets up a request for its list by placing the appropriate value in the register, DNLSTCOD, which the DOWNLINK will pick up as the ID. When, at the beginning of the next pass, the DOWNLINK reads this register, the appropriate list is then initiated (i.e., the list is not switched in the middle of a pass). This procedure is of course not true for the erasable memory dump downlist (see section 2.2.1), which completes its required number of passes irrespective of other programs. A computer "restart", or "fresh start" will immediately cause the telemetry list to start with word #1 . A "restart" will retain the list in progress but a "fresh start" will set the list to Coast and Align. An erasable memory dump, if in process, will be interrupted in both cases.

Since certain data on the standard downlink lists are only meaningful when considered in multiregister arrays and since the programs which compute these arrays are not synchronized with the downlink program, a "snapshot" is taken of these words so that changes in their values will not occur while these arrays are being transmitted to the ground. When a "snapshot" is taken several words are stored at the time the first word is transmitted. The other words in the downlist are read at the time of transmission and therefore the only time homogeneity for them is between the two registers making up a single word. The COLOSSUS downlists have the following "snapshots":

Powered List	words 2-8, 9-13, 52-58, 59-63
Coast and Align List	words 2-8, 9-13, 52-58, 59-63
Rendezvous and Prethrust List	words 2-8, 9-13, 52-58, 59-63
Entry and Update List	words 2-8, 9-13, 52-58, 59-63
P-22 List	words 2-8, 9-13, 52-54, 59-63

The following is a list of CMC registers making up the various downlists. A register may contain other quantities during programs in which the CMC no longer needs to save the primary downlist quantity.

2.2.2.1 Powered List

Word Number	Contents: First Register	Contents: Second Register
1	I.D. (77774_8)	Synch Bits (77340_8)
2	CSM State Vector (R_X)	CSM State Vector (R_X)
3	CSM State Vector (R_Y)	CSM State Vector (R_Y)
4	CSM State Vector (R_Z)	CSM State Vector (R_Z)
5	CSM State Vector (V_X)	CSM State Vector (V_X)
6	CSM State Vector (V_Y)	CSM State Vector (V_Y)
7	CSM State Vector (V_Z)	CSM State Vector (V_Z)
8	CSM State Vector Time	CSM State Vector Time
9	Actual X CDU angle	Actual Y CDU angle
10	Actual Z CDU angle	Optics CDU Trunnion Angle
11	ADOTS roll or OGARATE	ADOTS roll or OGARATE
12	ADOTS pitch or OMEGA B pitch	ADOTS pitch or OMEGA B pitch
13	ADOTS yaw or OMEGA B yaw	ADOTS yaw or OMEGA B yaw
14	X attitude error	Y attitude error
15	Z attitude error	RCS flags
16	THETADX	THETADY
17	THETADZ	Garbage
18	TIG	TIG
19	T_F Lambert	T_F Lambert
20	RTARGX	RTARGX
21	RTARGY	RTARGY
22	RTARGZ	RTARGZ
23	TGO	TGO
24	PIPTIME1	PIPTIME1
25	DELVX	DELVX
26	DELVY	DELVY
27	DELVZ	DELVZ
28	PACTOFF	YACTOFF
29	PCMD	YCMD
30	CSTEER	Garbage
31	Spare	Spare
32	Spare	Spare
33	Spare	Spare
34	REFSMMAT (R_1C_1)	REFSMMAT (R_1C_1)
35	REFSMMAT (R_1C_2)	REFSMMAT (R_1C_2)
36	REFSMMAT (R_1C_3)	REFSMMAT (R_1C_3)

Word Number	First Register	Second Register
37	REFSMMAT (R_2C_1)	REFSMMAT (R_2C_1)
38	REFSMMAT (R_2C_2)	REFSMMAT (R_2C_2)
39	REFSMMAT (R_2C_3)	REFSMMAT (R_2C_3)
40	Flagword 0	Flagword 1
41	Flagword 2	Flagword 3
42	Flagword 4	Flagword 5
43	Flagword 6	Flagword 7
44	Flagword 8	Flagword 9
45	DSPTAB+0	DSPTAB+1
46	DSPTAB+2	DSPTAB+3
47	DSPTAB+4	DSPTAB+5
48	DSPTAB+6	DSPTAB+7
49	DSPTAB+8D	DSPTAB+9D
50	DSPTAB+10D	DSPTAB+11D
51	TIME 2	TIME 1
52	LM State Vector (R_X)	LM State Vector (R_X)
53	LM State Vector (R_Y)	LM State Vector (R_Y)
54	LM State Vector (R_Z)	LM State Vector (R_Z)
55	LM State Vector (V_X)	LM State Vector (V_X)
56	LM State Vector (V_Y)	LM State Vector (V_Y)
57	LM State Vector (V_Z)	LM State Vector (V_Z)
58	LM State Vector Time	LM State Vector Time
59	Actual X CDU angle	Actual Y CDU angle
60	Actual Z CDU angle	Optics CDU trunnion angle
61	ADOTS roll or OGARATE	ADOTS roll or OGARATE
62	ADOTS pitch or Omega B pitch	ADOTS pitch or Omega B pitch
63	ADOTS yaw or Omega B yaw	ADOTS yaw or Omega B yaw
64	X attitude error	Y attitude error
65	Z attitude error	RCS flags
66	THETADX	THETADY
67	THETADZ	Garbage
68	* RSBBQ	RSBBQ+1
69	* CADRFLSH	CADRFLSH+1
70	* CADRFLSH+2	FAILREG
71	* FAILREG+1	FAILREG+2
72	Optics Shaft	PIPAX
73	PIPAY	PIPAZ

* Indicates two single precision quantities that are not indicated otherwise.

Word Number	First Register	Second Register
74	Elevation Angle	Elevation Angle
75	Central Angle	Central Angle
76	Offset Point	Offset Point
77	Flagword 10	Flagword 11
78	TEVENT	TEVENT
79	PCMD	YCMD
80	OPTMODES	HOLDFLAG
81	LM MASS	CM MASS
82	DAPDATR1	DAPDATR2
83	ERROR X	ERROR Y
84	ERROR Z	Garbage (THETADX)
85	WBODY (roll) or OMEGAC (roll)	WBODY (roll) or OMEGAC (roll)
86	WBODY (pitch) or OMEGAC (pitch)	WBODY (pitch) or OMEGAC (pitch)
87	WBODY (yaw) or OMEGAC (yaw)	WBODY (yaw) or OMEGAC (yaw)
88	REDO COUNTER	Desired FINAL CDUX
89	Desired FINAL CDUY	Desired FINAL CDUZ
90	IMODES 30	IMODES 33
91	Channel 11	Channel 12
92	Channel 13	Channel 14
93	Channel 30	Channel 31
94	Channel 32	Channel 33
95	VGTIGX	VGTIGX
96	VGTIGY	VGTIGY
97	VGTIGZ	VGTIGZ
98	Spare	Spare
99	Spare	Spare
100	Spare	Spare

2.2.2.2 Powered List

Word Number	Contents
1a	ID word for this list. It will contain 77774_8.
1b	Synch bits. It will contain 77340_8.
2-8	CSM STATE VECTOR and TIME. The CMC's latest calculated state vector for the CSM in either earth-centered or moon-centered reference coordinates. During the Orbital Integration Routine, the sphere of influence will be indicated by Flagword 8, bit 12 (CMOONFLG): zero = earth-centered; one = lunar-centered. It is important to note that the Average-G routine is initialized with a state in RN, VN which can have a different origin than is indicated by CMOONFLG. This means an inconsistency in the Downlink of the state vector actual origin and CMOONFLG origin. Words 2-4 contain the position components, X, Y, Z, scaled meters/2^{29}. Words 5-7 contain the velocity components, X, Y, Z, scaled (meters/centisecond)/2^7. Word 8 contains the time associated with the CSM state vector in words 2-7, scaled centiseconds/2^{28}, referenced to the computer clock. These parameters are calculated whenever the CSM state vector is permanently extrapolated or changed, as follows: P00 - every four time steps P20, P22, P23 - every mark and every Incorp if CM connected P27 - update of state vector Average G - every cycle V47
9 & 10a	CDUX (outer gimbal) CDUY (inner gimbal) CDUZ (middle gimbal): The actual values of the IMU CDU angles. Each register is an unsigned 15-bit fraction, scaled degrees/360, and is updated by counter interrupts. A middle gimbal angle greater than 70 degrees will light the Gimbal Lock lamp on the DSKY. Whenever the magnitude of the MGA exceeds 85 degrees the ISS stabilization loop will be disabled. As a result, the CDUZ register should maintain values that correspond to middle gimbal angles between -70 degrees and +70 degrees.
10b	CDUT. The optics trunnion angle CDU, scaled (degrees - 19.7754)/45 (two's complement). The angle varies from -19.775° to $+45^{\circ}$.
11-13	ADOTs (if RCS DAP on) or OGARATE and OMEGABs (if TVC DAP on). ADOTs are the RCS DAP - measured vehicle body rates (i.e. the outputs from the RCS DAP rate filter), roll, pitch and yaw, about the control axes. These axes are aligned with the RCS jet quads and, consequently, are rotated, with respect to the NAV base axes, -7.25 degrees about +X. ADOTs are scaled, (degrees/second)/450. OGARATE, in word 11, is the measured roll rate

Word Number	Contents
11-13 (cont)	obtained by back-differencing the outer gimbal angle (OGA) measurements every 0.5 second, scaled (rev/sec)/2^{-4}. This quantity will normally be near zero magnitude but a roll jet failed-on could produce 2-3^{o}/sec rates. OMEGABS, in words 12 and 13, are the measured pitch and yaw attitude rates about the body axes, obtained by back-differencing the CDU readings every TVC DAP sample period. The time sharing and scaling for OMEGABs are the same as for the OMEGACs, described in words 85-87 of this downlist. The maximum OMEGAB rate will be less than 5 deg/sec. NOTE: Even though the TVC zeroing loop treats OGARATE as a single precision quantity, it will be transmitted and considered as a double precision quantity in which the low-order register will always be zero. This is due to the fact that OGARATE = OMEGAXB and after zeroing OMEGAXB and OMEGAYB, as part of the TVC zeroing loop, OGARATE is computed and stored in DP.
14, 15a	AKs. The X, Y and Z (roll, pitch and yaw, respectively) attitude errors used to drive the FDAI display, scaled degrees/180. The roll attitude error register (AK +0) is loaded with one-quarter the "raw" value during P11 (and entry programs while Entry DAP is running, although the cell is not telemetered then) to increase the scale by a factor of four. The attitude errors are about the control axes for RCS DAP and about the body axes for TVC and Entry DAP. Zeros in bits 15, 14 and 13 of DAPDATR1 and a one in bit 2 of Flagword 6 indicate that the Entry DAP is active. During RCS DAP operation the particular error quantities depend upon the display mode selected, as follows: MODE 1 (selected by V61) results in Autopilot phase-plane errors; MODE 2 (selected by V62) results in total attitude errors with respect to the angles in N22; MODE 3 (selected by V63) results in total astronaut attitude errors with respect to the angles in N17. In MODE 1 the errors should generally remain less than the attitude deadband, ADB, (either 0.5 degree or 5 degrees as selected in DAPDATR1). The values are calculated every 200 ms during RCS DAP operation, whereas in TVC DAP operation, AK is updated every 0.5 second in TVC EXECUTIVE with the current value of OGA, and AK 1 and AK 2 are updated every TVC DAP sample period (in PCOPY and YCOPY) with the respective values of ERRBTMP. Also, with TVC DAP, AK will normally have a magnitude of less than 5 degrees but a jet failed-on could produce up to 30 degrees. AK 1 and AK 2 will normally have peak values of up to 10 degrees, converging to 0-4 degrees with time.

Word Number	Contents
15b	RCSFLAGS. A cell whose individual bits are used in monitoring the RCS.

Bit	Meaning
15	Bit set 1 to indicate a high rate (4 deg/sec) auto maneuver in progress. Bit is reset to 0 to indicate that a high-rate auto maneuver is not in progress.
14	Bit set 1 if rate estimates are not good. Repeat initialization of rate filter. Bit is reset to 0 if the rate estimates are good.
13	Bit set 1 if the rate damping has not been completed on the roll axis. Bit is reset to 0 if the rate damping on the roll axis has been completed.
12	Bit set 1 if the rate damping has not been completed on the pitch axis. Bit is reset to 0 if the rate damping has been completed on the pitch axis.
11	Bit set 1 if the rate damping has not been completed on the yaw axis. Bit reset to 0 if the rate damping has been completed on the yaw axis.
10, 9	If either or both bits have been set to 1, there has been a change in RHC roll command since the last DAP cycle. If both bits are reset to 0, it implies that no change in the RHC roll command has occurred since the last DAP cycle.
8, 7	If either or both bits have been set to 1, there has been a change in RHC yaw command since the last DAP cycle. If both bits are reset to 0, it implies that no change in the RHC yaw command has occurred since the last DAP cycle.
6, 5	If either or both bits have been set to 1, there has been a change in the RHC pitch command since the last DAP cycle. If both bits are reset to 0, it implies that no change in the RHC pitch command has occurred since the last DAP cycle.
4	Bit set 1 indicates that the AK values should be updated. Bit is reset to 0 to indicate that the NEEDLE DRIVE routine should be processed. with the AK values which have been previously acquired.

Word Number	Contents	
15b (cont)	Bit	Meaning
	3, 2	If Bit 3, Bit 2 = 11 or 10, it is necessary to follow the initialization path of the NEEDLE DRIVE routine. If Bit 3, Bit 2 = 01, it is necessary to follow pass 2 of the NEEDLE DRIVE routine. If Bit 3, Bit 2 = 00, it is necessary to follow pass 3 and greater paths of the NEEDLE DRIVE routine.
	1	Bit is set 1 to indicate that the initial pass path in the T6 program should not be followed. Bit is reset to 0 if the T6 program should be initialized.

16-17a THETADX, THETADY, THETADZ. During normal RCS DAP operation, when the CMC Mode switch is in AUTO or HOLD and there are no RHC commands, these registers contain the desired current, (i.e., of this DAP cycle opposed to final) roll, pitch, and yaw CDU angles, treated as 15-bit unsigned fractions and scaled degrees/360. These quantities are used in the computation of phase plane attitude errors and are calculated as follows:

1. During automatic maneuvers they are updated every 100 milliseconds.
2. During attitude hold they are constants (the desired CDU angles to be held).
3. At the end of manual rate maneuvers, after rate damping is complete, THETADX, Y & Z are set to the current CDU angles.
4. During manual rate maneuvers and when in FREE mode the registers are not updated.

17b Garbage. This register is used in TVC Zeroing (P40) by the item, C5, which is the yaw TVC CSM/LM filter (5th node). It also may contain DELCDUX, the high-order part of the double-precision quantity which is the incremental value used in the THETADX computation during automatic maneuvers.

18 TIG. The time of ignition (prethrust) or time of cutoff (while thrusting). The changeover in definition occurs at ignition if an impulsive burn and at first TGOCALC (nominal TIG+2) if steering. This item is scaled, centiseconds/2^{28}. It undergoes a single-shot

Word Number	Contents
18 (cont)	calculation by P39, P34 and P35 (prethrust, time of ignition); a single-shot update by P40 for slipped TIG when integration for AVE G cannot be completed in time (time of ignition); a single-shot computation of the time of engine cutoff by P40 impulsive burn logic; or two-second updates of time to engine cutoff, initiated at the first steering pass (nominal TIG+2). Upon engine failure, the most significant half of TIG is set to -24_8 and the least significant half remains unchanged.
19	DELLT4 (The desired transfer time) The time from TIG until the target (RTARG) is reached, scaled centiseconds/ 2^{28}. It is used as an input to the INITVEL subroutine and calculated by each user of this subroutine.
20-22	RTARG. The aimpoint vector X, Y, Z, in either earth-centered or lunar-centered coordinates and scaled meters/2^{29}. The origin of the coordinate system is the same as that of the CSM state vector at TIG. Caution must be exercised in ground/AGC communications whenever the spacecraft is operating near the "sphere-of-influence" switchover point. Bit 12, flagword 8 (CMOONFLG) indicates whether the CSM state vector is earth- or moon-centered. This parameter is calculated in P34/P74, P35/P75, P38/P39, P78/P79 and updated in the Initial Velocity Subroutine.
23	TGO. The time to go until engine cutoff, scaled centiseconds/2^{28}. At TIG-5, for an impulsive burn (TGO < 6) TGO is calculated once and represents the time from now until engine cutoff. If the estimated maneuver time is greater than six seconds, active steering is used and TGO becomes the length of time from the last PIPA reading to engine cutoff. During this steering burn, TGO is calculated each two seconds from start steer to stop steer. Start steer begins at TIG+2 for nominal TIG-0 ignition and at TIG+4 for slipped ignition.
24	PIPTIME1. The time (T2/T1) at which the PIPAs are read, scaled centiseconds/2^{28}. Integration stores the preread state vector time in anticipation of reading PIPAs at that time. PIPASR stores TIME2/TIME1 every two seconds during Average g (TIG-30 to P40/41 exit; etc.). Since the group is not a snapshot quantity, their values as transmitted may not be valid simultaneously.

Word Number	Contents
25-27	DELVs. The sampled X, Y, & Z PIPA accumulations (velocity increments) with compensation for PIPA bias and scale factor errors. These quantities are in the stable member coordinate system and are scaled, $(cm/sec)/(5.85 \times 2^{14})$. Calculation takes place every two seconds during AVE G. The variation with time and the range of values depend on the acceleration level and compensation. There is a zeroing of all low-order components and a momentary zeroing of DELVY and DELVZ prior to the loading of PIPA contents into respective high-order words (part of READACCS, or REREADAC task). PIPA compensation follows in Servicer job (inhinted, so that all or not PIPA compensation shows up).
28	PACTOFF (pitch), YACTOFF (yaw). The SPS engine gimbal-actuator trim angle estimates in the pitch and yaw planes (used to align the engine with the vehicle cg), scaled (seconds of arc)/(85.41×2^{14}). These values are added to the DAP filter output every DAP sample period as part of the engine gimbal servo command. The variation is usually less than ±2 degrees over the course of a burn. These are the upper halves of the double-precision registers, PDELOFF and YDELOFF. These items are set initially by astronauts in P40 (R03). They change significantly at switchover which is about 3.4 seconds after ignition for CSM; 6.4 seconds for CSM/LM. Incremental changes are made every 0.5 second after switchover and an end-of-burn update is made following the engine shut-down command.
29	PCMD (pitch), YCMD (yaw). The pitch and yaw SPS engine gimbal-actuator position commands from the respective TVC DAPs, scaled (seconds of arc)/(85.41×2^{14}). The expected range of values is between ±1 degree, while the maximum possible values are ±6 degrees. They are calculated at every TVC DAP sample period: 40 ms for CSM, 40, 80 ms for CSM/LM.
30	CSTEER. The Cross Product Steering Constant, "c", used by P40/P1 in the equation $\Delta m = c\underline{b}\Delta t - \Delta\underline{v}$ and certain prethrust computations. It is scaled "c"/4. The least significant half of this word will always be made a + 0 whenever CSTEER is set to ECSTEER or zeroed. The value range will be from -4 to +4 (less one bit). It is set by P40 prethrust to ECSTEER if a Lambert burn. It will be zeroed by P40 prethrust if an external ΔV burn and also by P41 prethrust.

Word Number	Contents
31-33	Spares. The first half of each spare contains 00000_8. The second half is ARUPT (the contents of the accumulator when the telemetry interrupt was recognized.
34-39	REFSMMAT. Six elements of REFSMMAT, double precision quantities, transmitted R_1C_1, R_1C_2, R_1C_3, R_2C_2, and R_2C_3, each scaled 2^{-1}. REFSMMAT is the 3×3 matrix used to convert between reference coordinates and stable member coordinates. The remaining three components of REFSMMAT may be computed as follows: $R_3C_1 = (R_1C_2)(R_2C_3) - (R_1C_3)(R_2C_2)$ $R_3C_2 = (R_1C_3)(R_2C_1) - (R_1C_1)(R_2C_3)$ $R_3C_3 = (R_1C_1)(R_2C_2) - (R_1C_2)(R_2C_1)$, where R = ROW and C = COLUMN. REFSMMAT is calculated in P51, P52, P53 and P54.
40-44	TEN FLAGWORDS (0, 1, ... 9). Bit assignments are as follows:

Flagword	Bit	Meaning
0	15	Not used. Should always be 0.
0	14	JSWITCH. Bit set to 1 within orbital integration routine to indicate that extrapolation of W-matrix is being carried out in orbital integration routine (in contrast to the state vector extrapolation likewise done by the routine). Would only become 1 if bit 1 of FLAGWRD3 were 1.
0	13	MIDFLAG. Set to 1 within orbital integration routine at beginning of time step when magnitude of conic position vector is greater than the constants RME (earth-centered) or RMM (moon-centered) and set to 0 if less than these constants. If MIDFLAG is set to 1 integration will include secondary body and solar perturbations to the orbit.

Flagword	Bit	Meaning
0	12	MOONFLAG. Set by orbital integration to 1 or 0 when integrating the stored CSM and LM state vectors; 1 indicates lunar orbit, 0 indicates earth orbit. Also set to 1 or 0 in integration when switching coordinate centers. MOONFLAG is also set to 1 or 0 by callers of INTEGRVS which specify the state vector to be integrated and in P27, P76, V67 and V47 when using integration subroutine to permanently store state vectors.
0	11	NORFHOR. A 1 indicates far horizon. A 0 indicates near horizon. Set to 0 or 1 in P23 from astronaut input of near or far horizon. Used to determine which point of tangency equation is to be used (near or far).
0	10	ZMEASURE. A 1 indicates measurement planet and primary planet different. A 0 indicates measurement planet and primary planet the same. Set 0 in P23 when state vector sphere of influence and sighting planet measurement are in the same sphere of influence; otherwise set to 1. Used in P23 to pick up the vector difference between state vector and landmark vector.
0	9	NEEDLFLG. Bit set 1 by a verb 62 or verb 63 and set 0 by a verb 61 (or by a fresh start), used to control the information presented on the FDAI attitude error needles by the RCS DAP (it has no effect on the TVC or Entry DAP's.) If the bit is 1 and in addition the N22ORN17 bit (bit 6 of flagword 9) is 1, "total attitude error" with respect to the contents of N22 is displayed, defined as THETAD - CDU resolved into roll pitch and yaw coordinates. If the bit is 1 and in addition the N22ORN17 bit is 0, "total astronaut attitude error" with respect to the contents of N17, is displayed, defined as CPHIX - CDU resolved into roll pitch and yaw coordinates. CPHIX can be loaded with the present CDU angles by a verb 60. If the bit is 0, then, independent of other bit settings, RCS DAP phase-plane errors, ERRORX, ERRORY, and ERRORZ, which are some times called "autopilot following errors" are displayed. Polarity of the error. is, as in the other displays, desired minus actual. The "total attitude error" and the "total astronaut attitude error" are defined as a difference between "present" attitude and

Flagword	Bit	Meaning
0 (cont)	9	an attitude specified in N22 or N17. Consequently, these attitude errors may assume large values. The phase plane attitude errors, however, are quantities used by the RCS DAP to command jet firings when the CMC MODE SWITCH is in AUTO and HOLD and thus should generally remain within the selected RCS DAP attitude deadband.
0	8	IMUSE. Bit set 1 to indicate that "IMU is in use". It is set 0 each time a verb 37 program change is processed (unless bit 7 of this word is 1), and is set 1 when routine 02 is performed (at the start of P20, P22, P40, P41, P47, P52 and P54). It is also set 1 if the IMU is on at the start of P51 and P53 (if IMU not on, P05 is requested), and also when the IMU CDU zeroing subroutine is performed (verb 40 noun 20 or during IMU prelaunch initialization), provided in the latter case that the program number was not 0 (it would not be for the P01 IMU prelaunch initialization, of course). If the bit is 1 and the IMU is turned off, alarm 0214_8 is generated. Bit not set at start of P61 or P62.
0	7	RNDVZFLG. Bit set 1 to indicate that program P20 (Rendezvous Navigation) is "running". It is set to 1 shortly after a verb 37 input of P20 (coming e.g. from P00), and causes a restart to transfer to "P1KUP20" if encountered at any time when the bit is 1 (subsequent computations, however, may be negligible). The bit is set 0 by a verb 56, by a verb 37 input of P00, by P06, or by a verb 37 input of P20 if the bit is 1 (this would cause a re-intiation of P20 functions). If the bit is 1, the value of bit 8 of this word is not changed if a V37 input is received (other than P00, of course). If a V37 input of P20 is received with the present program being other than P20, performance starting at "P1KUP20" is enabled, with bits 7 and 5 of FLAGWRD1 being set 1. Start of P22 and P23 sets bit 0.
0	6	R53FLAG. Bit set 1 to indicate that a request for optics marks (flashing verb 51) has been initiated by routine 21 (used with routine 22 for P20) or by routine 53 (used with P22, P51, and P52). Bit is reset 0 at start of routine 52 (for use in logic that causes routine 53 to be initiated if optics mode not "computer control"), and is also set 0 at

Flagword	Bit	Meaning
0	6	the end of routine 21 (after the "enter" indicating termination of marks) and routine 53 (after the completion of marks if some were taken and landmark tracking, and after the reconfirmation of the star used if marks taken and star tracking).
0	5	F2RTE. A 1 means Return to Earth Targeting is operating in the time-critical mode. A 0 means Return to Earth Targeting is operating in the fuel-critical mode. In the time-critical mode the program generates a trajectory which meets the re-entry constraints and returns the spacecraft in the shortest possible time. In the fuel critical mode the program generates a trajectory which meets the re-entry constraints and minimizes the impulsive velocity change required to achieve this trajectory. Bit set 0 if the astronaut sets the desired velocity change (ΔV_D) equal to 0 or to a value less than the minimum required impulsive velocity change. Otherwise a time-critical trajectory is provided (bit set 1). Bit is set and tested in P37.
0	4	TRUNFLAG. Bit set 1 to indicate that driving of optics trunnion allowed in R52 (due to fact that desired trunnion angle is not greater than 50° and is not less than 0°). If not tracking the LM and trunnion angle exceeds 90° (bit 7 of FLAGWRD3), alarm 0404_8 is generated. If desired trunnion angle is more than 50° but less than 90°, alarm 0407_8 is generated. The allowable driving refers to location of object being sighted (actual loading of desired optics interface cells takes place only if optics in Computer Control Mode). Driving of the optics shaft (loading of "desired shaft angle" cell) takes place regardless of the value of the TRUNFLAG bit; driving of both takes place in a routine entered every 0.48 second ("T4RUPT" package), and is subject to optics moding constraints there. Bit set 1 at start of routine 52, but required setting is re-evaluated each time a new value of desired optics angles is computed.
0	3	FREEFLAG. Bit used for temporary program control purposes to control the internal performance of a subroutine. Also used in routine 54 (likewise P51-P54) to control performance of star data check routine, where it is initialized to 1 and set to 0 if V32E performed for V06N05 display.

Flagword	Bit	Meaning
0	2	Not used.
0	1	KFLAG. A 1 indicates preferred central angle search sector less than 180^{o}. A 0 indicates greater than 180^{o}. Set 1 or 0 in P17.1 and/or S17.1. Tested in P17.1 and S17.2.
1	15	NJETSFLG. Bit set 1 in routine 03 (entered via verb 48) if bits 10 and 7 of DAPDATR1 are not equal, indicating that two-jet X translation is specified (setting also made if DAP initiation is required, e.g. transition between TVC and RCS DAP or DAP start-up, so DAPDATR1 could have been changed by V21N46 means). If these bits are equal, bit is set 0, indicating 4-jet X translation. The bit (i.e. #15) is used in the computation of the burn interval required in the "time burn" test done 5 seconds before ignition in P40, and for P41 X-axis thrust.
1	14	STIKFLAG. Bit set 1 in RCS DAP computations if bits 6-1 of channel 31 (rotational hand controller inputs used for either attitude rate commands (not in free mode) or for angular acceleration commands (in free) are not 77_{8}. STIKFLAG set to 1 means that the astronaut has assumed rotational control of the S/C and P20 automatic tracking is inhibited. The uplink activity light will be lighted during this period if the present and requested gimbal angles differ by more than 10 degrees. The bit is reset to 0 by an input of V58 and V37.
1	13	ERADFLAG. Bit set 1 to specify that a coordinate transformation should use the Fischer ellipsoid for determining earth radius, and set 0 to specify that the pad radius (6 373 338 meters should be used. If the moon is the sphere of influence then bit set to 1 to use fixed lunar radius (1 738 090 meters) and bit set to 0 to use the magnitude of the lunar landing site (RLS) as the lunar radius. A value of 1 is set in P22 in conjunction with the computation of landmark positions (a value of 0 is used in routine 52 for optics pointing computations, however, in this program); a value of 0 is set in P11, P21, when routine 30 computations are carried out, and in entry.
1	12	Not used.

Flagword	Bit	Meaning
1	11	ENG2FLAG. SPS/RCS thrust indication for prethrust burn attitude computations. Set 1 by P41 to indicate RCS thrust levels. Cleared to 0 by P40 to indicate SPS thrust levels.
1	10	TARG1FLG. Bit set 1 in "REDOP20" (see bit 7 of FLAGWRDO) after the initial performance of routine 61, to indicate to routine 52 that tracking of the LM as a target (in contrast to a star or landmark) is required. Bit is set 0 each time a verb 37 program change is processed, as well as when R51 is entered (P52 or P54), or P22.
1	9	Bit has two distinct functions, hence two difference mnemonics. TARG2FLG. Bit set 1 at start of P22 to flag the fact (combined with bit 10 = 0) that tracking of a landmark is required by routine 52. Bit is set 0 in P52, P54 (indicating, with bit 10 = 0, that tracking of a star is required). R23FLG. Bit set 1 by extended V54 (COAS MARKING) reset 0 by extended V57 (regular optics marking). Communication to R22 as to which marking system is operating.
1	8	VEHUPFLG. Bit set 1 to specify that CSM state vector is to be updated by rendezvous (or orbital) navigation measurements; a value of 0 means that the LM state vector is to be updated. Average G always updates the CSM state vector; routine 32 (entered via verb 84) always updates the LM state vector. Bit can be set to 1 by a verb 81, and to 0 by a verb 80. Bit cleared at the start of P20. Bit is set to 1 in P22 just before the computation of state vector change due to landmark measurement (which is followed by the V06N49 display).
1	7	UPDATFLG. Bit set to 1 to indicate that updating of state (in P20) vector by marks is allowed. Bit is set 0 each time a verb 37 program change is processed, but is set 1 again at the start of P20 (or if bit 7 of FLAGWRDO = 1), and at the start of P17, 30, 31, 34, 35, 38, 39 74, 75, 77, 78, and 79. It is set 0 for a "proceed" input to the V16N45 flash in P34/P74 (indicating that the "final" computation cycle selected). The setting to 1 based on bit 7 of FLAGWRDO only takes place if the previous program was not P20 but the new one specified

Flagword	Bit	Meaning
1 (cont)	7	is P20. Bit also set to 0 at the start of P41, P52, and P54 (the setting is redundant since the V37 processing logic leaves the bit 0 anyhow). Bit also set 0 by an input of verb 56, and by the Target Delta V Routine (R32). It is also reset and set during the prethrust computations to protect erasable memory. A value of 0 causes the P20 state vector update to be bypassed.
1	6	IDLEFAIL. Set 1 in R40 routine in response to the astronaut PROCEED response to the flashing V97. A 1 will inhibit setting up the flashing V97 again for at least 2 seconds. Set 0 in V37 2 seconds after the astronaut ENTER response to the flashing V97. A 0 will permit R40 to set up another flashing V97. Tested in LOTHRUST exit from cross product steering routine.
1	5	TRACKFLG. Bit set to 1 to indicate that performance of P20 is allowed (including automatic attitude maneuvers and optics pointing). Set to 1 at the same times as bit 7 of FLAGWRD1, and reset to 0 each time a verb 37 program change is processed, as well as by an input of verb 56. If bit becomes 0 (e.g. via verb 56), then computations of routine 22 and Routine 52 for this tracking are halted. An attempt to initiate (via verb 57) the performance of R21 or R23 is rejected (alarm 0406_8) unless both this bit and bit 7 of FLAGWRDO are 1. Bit also set 0 if IMU coarse aligned or caged & start P52/P54.
1	4	TRMO3FLG. Bit set 1 when request made to terminate P03 before P03 is completed. Otherwise bit set 0.
1	3	SLOPESW. Set to 1 at the start of the LAMBERT routine, and reset to 0 at the end of the first pass through the internal LAMBERT iteration process (specifically, inside the ITERATOR subroutine, which calculates the increment to be added to the independent variable for use on the next pass). The bit controls the type of computation performed in the ITERATOR subroutine. If the first pass through the internal LAMBERT iteration process yield satisfactory results, however, so that additional passes are not required (which will generally only occur when a very good guess of the independent

Flagword	Bit	Meaning
1	3	variable is input to LAMBERT, such as occasionally during powered-flight guidance computation sequencing), then ITERATOR is not called, and consequently the bit is left set to 1 when LAMBERT is exited. This bit is equivalent to the switch f_3 of Section 5.5 of this GSOP.
1	2	GUESSW. Set to 1 to indicate to the LAMBERT routine that an initial guess of the independent variable used in the internal LAMBERT iteration process is not available, thus forcing LAMBERT to start iterating from the mid-point of the range of the independent variable. The bit is set to 0 to indicate to LAMBERT that an initial guess is available; this will in general greatly reduce the number of iterations and the computation time inside LAMBERT. The Initial Velocity Subroutine INITVEL always sets the bit to 0 internally immediately after it calls LAMBERT, whether or not INITVEL is in its conic mode (as during powered-flight guidance computation sequencing) or its precision mode (as during targeting). The bit is also set to 1 by INITVEL, but only when INITVEL is entered via a special entrance. This special entrance is used only by the Pre-TPI Maneuver Program P34/P74, the Pre-TPM Maneuver Program P35/P75, and the Lambert Aim-Point Maneuver Pre-Thrust Computation Routine. This bit is equivalent to the switch f_1 in Section 5.5 of this GSOP.
1	1	AVEGFLAG. Bit set 1 to permit cycling of Average-G computations to continue at a two-second rate, and reset to 0 to halt this cycling and cause initial conditions to be set for a period of free-flight operation. Bit is set 0 by the processing of a V37 input if bit 6 of FLAGWRD7 = 1 (the V37 processing is then resumed when the Average-G routime detects bit 1 of FLAGWRD1 = 0 and has completed the necessary initializations: consequently, Average-G is always terminated when a V37 input is acted upon). Bit is set 1 when Average-G is "started" (after state vector initialization in P11, about 30.5 seconds before ignition for P40, about 15 seconds before nominal ignition for P41, and about a minute after input of the program number for P47 and P61 or P62).

Flagword	Bit	Meaning
2	15	DRIFTFLG. Bit set 1 to enable free-flight gyro drift compensation, and set to 0 in order to disable it (if bit is 1, a job is established every 81.93 seconds by taking advantage of some waitlist control logic). Bit is set 1 when Average-G is terminated and also in P51/P53 before taking optics marks and in P52/P54 after completion of coarse align (if performed). Bit set 0 if IMU coarse aligned or caged, and when Average-G started.
2	14	R21MARK. Bit set 1 when routine 21 is entered via verb 57 in order to specify to optics mark reception routine that different processing for optics marks from that normally (e.g. P51 or P22) done is required. Bit is reset to 0 when R21 is terminated (e.g. at completion of desired marks).
2	13	22DSPFLG. A 1 means display ΔR and ΔV which are computed by the measurement incorporation routine for astronaut approval. A 0 means do not display. Set 1 in P22 prior to displaying the ΔR and ΔV values which are computed from the first set of mark data. Tested after the first ΔR and ΔV are computed, then cleared to 0 for the remainder of the present operation of P22.
2	12	Not used.
2	11	STEERSW. A 1 indicates that cross-product steering and time-to-engine cutoff computations are to be made. A 0 indicates these computations are to be bypassed. Cleared by V37. If non-impulsive burn then set 1 two seconds after ignition (see STRULLSW). Cleared when computed time-to-engine cutoff drops below 4 seconds. Cleared when thrust-failure is detected (R40), set 1 again only if astronaut responds to the flashing V97 display with a PROCEED (continue the burn).
2	10	Not used.
2	9	IMPULSW. An indication of "impulsive burn" conditions. Set 1 unconditionally by the TIG-5 "timeburn" calculations, cleared to 0 only if the burn is to be non-impulsive (longer than 6 seconds so that cross product steering and T60 computations can be made). Bit then tested at ignition: if 0 steering will be enabled 2 seconds later; if 1 the SPS engine

Flagword	Bit	Meaning
2 (cont)	9	cutoff routine is scheduled at the appropriate time (thrust on time as predicted by the timeburn routine) and IMPULSW is cleared to 0. In non-impulsive steering burns IMPULSW is set 1 when the computed time to engine cutoff falls below four seconds. This will result in the scheduling of the SPS engine cutoff routine for the appropriate time; IMPULSW is cleared to 0 when the scheduling is completed to prevent multiple scheduling. (In the event of thrust failure detection by R40 the timeburn calculations will be scheduled, impulsive re-ignition is handled normally.)
2	8	XDELVFLG. An indication of targeting/guidance type: 1 for external delta-V; 0 for Lambert. Set 1 by External Delta-V Targeting Program (P30). Cleared to 0 by all Lambert targeting programs.
2	7	Bit used for three distinct functions, hence assigned three separate mnemonics. ETPIFLAG. A 1 means an elevation angle has been input to P34/P74 and that TPI time is to be computed. A 0 means that TPI time is input and an elevation angle is to be computed. Bit set 1 on PROCEED response to V06N55 display with R2 = 0. FIRSTFLG. A 1 means initialization pass for Lambert targeting in P40. A 0 means not initialization pass. Set 1 during pre-thrust in P40/P41. Set 0 when Lambert starts about TIG -30 seconds. Tested every Lambert update. OPTNSW. A 1 means SOI phase of P38/P78. A 0 means SOR phase of P38/P78. Set 1 at PROCEED response to V04N06 display if option code in R2 is 1 (SOI phase), set 0 if R2 is 2 (SOR phase).
2	6	FINALFLG. Set 1 in P34/P74, P35/P75, P38/P78, P39/P79, P37 for a PROCEED response to the V16N45 display if FINALFLG is 0. Initialized to 0 at the start of P34/P74, P35/P75, P38/P78, P39/P79, P37. Set 0 if it has a value of 1 and the PROCEED response to the V16N45 display is taken. The N45 display has R3 set to -00001 if this bit is 0.

Flagword	Bit	Meaning
2	5	AVFLAG. Bit set 1 at start of P74, P75, P77, P78, P79 to indicate that the LM is the active vehicle. Bit set 0 at start of P34, P35, P78, P79, P17 to indicate that the CSM is the active vehicle.
2	4	PFRATFLG. Bit set 1 in P40 and P41 just before the V06N22 display of gimbal angles, after computations of the "preferred IMU orientation" for the burn. Bit is reset to 0 in P52 or P54 of routine R51.
2	3	CALCMAN3. Bit set to 1 in large attitude maneuver routine. Originally intended to indicate whether final roll maneuver was required, but, since automatic gimbal-lock avoidance has been eliminated, this bit actually is functionless.
2	2	CALCMAN2. Bit set 1 at end of large attitude calculation of maneuver parameters and reset zero after some computations concerning initial conditions for generation of the commands have been completed. Bit signifies that first iteration through the command generation equations is being performed; depending on phasing of the telemetry output with respect to the guidance computations, the "1" setting may or may not be observed on the downlink.
2	1	NODOFLAG. Bit set 1 to cause inputs of program numbers other than 00 (via V37 means) to be rejected unless TVC DAP, or SPS engine, is on, in which case new program number automatically made 0. Bit set 0 if R00 or in the processing of the V37 input if number of new program is 0. Bit is set 1 in P62 after the entry DAP is initialized (shortly after the "enter" response to checklist code 00041_8).
3	15	Not used.
3	14	GLOKFAIL. Bit set 1 when the CALCGA routine computes a middle gimbal angle in excess of 60°. A code 401_8 program alarm is then issued by CALCGA. GLOKFAIL is tested (and then reset to 0) by the IMU Calibration and Prelaunch Alignment Programs to determine the feasibility of requested IMU positions. Flight Programs P52, P54, P61 and P62 call CALCGA, however, they do not test GLOKFAIL, but a 401 alarm is possible.

Flagword	Bit	Meaning
3	13	REFSMFLG. Bit set 1 if a meaningful [REFSMMAT] (reference to stable member matrix) is available, i.e. the alignment of the IMU is known in inertial (reference coordinates) space. Bit set 1 in P11 shortly after liftoff deduced (and after [REFSMMAT] loaded). Bit is set 0 if the IMU is coarse aligned or caged, and is also set 0 for normal sequences through P05 and P06. Bit is set 0 briefly in P51 and P53 while the IMU orientation information obtained from star sightings is being loaded into [REFSMMAT], and is then set back to 1 (just before transfer to "GOTOPOOH" at the end of the program). In P52 or P54, bit would be set 0 if routine R50 performed coarse align, and bit is set 1 just before the checklist flash of 00015_8 to perform star acquisition: bit is not set 0 while new values being loaded into [REFSMMAT] in routine R50, so that restart protection of P51 and P53 not applicable here. If [REFSMMAT] option selected for P52 or P54, the bit is not set 1, but instead is left at 1 (since if bit is 0 when P52 or P54 selected, then P51 is requested if the IMU is on).
3	12	LUNAFLAG. Used in lat-long subroutine. A 1 means lunar lat-long. A 0 means earth lat-long. Set to 0 or 1 by routines that call lat-long subroutine.
3	11	P22MKFLG. A 1 means the block of landmark data on the P22 downlist is valid. A 0 means not valid. Set 0 upon entry to P22. Set 1 in P22 after the mark data which is taken upon the present landmark has been moved from a VAC area to the SVMRKDAT table in erasable memory to avoid loss of data if a restart occurs.
3	10	VFLAG. Bit initialized to 1 at the beginning of the star selection routine (entered by P52 and P54), and reset to 0 if a pair of stars found that satisfy all criteria. If bit is still 1 at the end of the star table search, alarm 0405_8 is displayed. Cell used for program control purposes (temporarily set 1, then back to 0) within star table search program after the first pair found.

Flagword	Bit	Meaning
3	9	Not used.
3	8	PRECIFLG. Set to 1 in the integration routine on calls to CSMPREC, LEMPREC, INTEGRVS, and in P00 when integrating LM. Set to 0 when completing integration and in P00 when integrating CSM. PRECIFLG = 0 engages 4 time step logic in integration when major mode is 00.
3	7	CULTFLAG. Bit used in automatic star selection routine (performed with P52 and P54) as an indicator (if 1) that the particular star being checked is too close to the computed positions of the earth (about 4 minutes after response to the checklist code 00015_8), sun, or moon. Bit also used in optics angle coordinate transformation routine to indicate (if bit 1 when return from the routine) that the indicated sextant trunnion angle required is in excess of 90°: this setting is used in the automatic optics positioning routine (R52) to bypass drive of the trunnion, as well as to generate priority alarm 0404_8 if LM not being tracked. Bit otherwise set 0 by routine.
3	6	ORBWFLAG. Bit set 1 if W-Matrix is considered valid for use in performing orbital navigation. Bit 1 of flagword 5 is used for the analogous function with rendezvous navigation. In P22 and P23 bit is set 1 for a valid W-Matrix and 0 for an invalid W-Matrix. Set 0 in P27 after receipt of a CSM state vector update, at the start of P20 and in P22 if the reduction of the W-Matrix to 6×6 form after completion of the mark information for a given object overflows. Set 0 in orbital integration if overflow occurs when integrating the W-Matrix. Set 0 in V67 following an ENTER followed by PROCEED on N99 display. Tested in AVETOMID: if bit 1 the 6×6 W-Matrix is integrated to PIPTIME using CSM state vector. Also tested in P00 periodic integration: if 1, 6×6 W-Matrix is integrated to CSM state vector time (TETCSM) using CSM state vector.
3	5	STATEFLG. Set to 1 if the permanent state vector is to be updated by orbital integration. Bit is checked after completion of integration (either CSM or LM) and if it is 1 it is reset to 0 and the appropriate loading of permanent and downlink state vectors (either CSM or LM) is

Flagword	Bit	Meaning
3 (cont)	5	accomplished. Also set to 0 after V96 if QUITFLAG is 1. Set to 1 if W-Matrix integration overflows. Set to 1 for periodic integration in P00 (LM and CSM) and to 0 if P00 integration not to be done (QUITFLAG = 1). Set to 1 in P22, P23 and P20 for integration to mark time and to cause permanent integration on initial operation of P20.
3	4	INTYPFLG. Set to 1 if conic extrapolation to be done in orbital integration, set to 0 for precision extrapolation.
3	3	VINTFLAG. Set to 1 if CSM state vector to be integrated; set to 0 if LM state vector to be integrated. Set internally in integration on calls via CSMPREC (conic), LEMPREC (conic) and by callers of INTEGRV and INTEGRVS.
3	2	D6OR9FLG. Used by orbital integration for W-Matrix integration. A 1 means 9×9 W-Matrix is integrated for P22. A 0 means 6×6 W-Matrix is integrated for P20, P23.
3	1	DIMOFLAG. Used by orbital integration for W-Matrix integration. A 1 means W-Matrix to be integrated. A 0 means no W-Matrix integration to be done.
4	15	MRKIDFLG. Set to 1 if a mark/extended verb display is waiting for a response: it signifies that a display of this type is in the "ENDIDLE" routine of the DSKY package ("pinball").
4	14	PRIODFLG. Set to 1 if a priority display is waiting for a response. It signifies that a display of this type is in the "ENDIDLE" routine of the DSKY package.
4	13	NRMIDFLG. Set to 1 if a normal display (most of the displays in the program are in this category) is waiting for a response: it signifies that a display of this type is in the "ENDIDLE" routine of the DSKY package.
4	12	PDSPFLAG. Set to 1 to indicate a priority display status exists. This will lock out mark displays and normal displays.
4	11	MWAITFLG. Bit included in logic assignments to permit function similar to bit 10 to be applied to mark/extended verb displays, but bit is not set by program. Consequently, bit is expected to remain 0.

Flagword	Bit	Meaning
4	10	NWAITFLG. Set to 1 if a normal display is waiting to be initiated (e.g. program attempts to initiate a normal display when an extended verb or mark display is occupying the DSKY). Helps give DSKY sequence of crew-initiated display, crew-initiated monitor display, priority display, interrupted mark/extended verb display, interrupted normal display, and waiting normal display.
4	9	MRKNVFLG. Set to 1 if a mark/extended verb display attempt found the display system busy (due to crew or uplink use for a display, including an externally initiated monitor display). Bit reset after appropriate display initiated (following key release response).
4	8	NRMNVFLG. Set to 1 if a normal display attempt found the display system busy (cf. bit 9).
4	7	PRONVFLG. Set to 1 if a priority display attempt found the display system busy (cf. bit 9).
4	6	PINBRFLG. Set to 1 if it is concluded that "interference" with the internally generated display has taken place (e.g. an enter verb was used but the associated noun was not that requested by the program when the internally generated display was produced), or if a termination for an extended verb/mark routine is performed with bit 13 of this word = 1. Bit reset 0 upon successful conclusion of a priority or normal display after having been used to bypass internal checks that otherwise would cause a program abort.
4	5	MRUPTFLG. Set to 1 if a mark/extended verb display or display attempt has been interrupted by a priority display.
4	4	NRUPTFLG. Set to 1 if a normal display or display attempt has been interrupted by a priority display or by a mark/extended verb display.
4	3	MKOVFLAG. Set to 1 briefly if a mark/extended verb display is to interrupt a normal display (used to control internal program branching, whereupon it is reset to 0).
4	2	Not used.

Flagword	Bit	Meaning
4	1	XDSPFLAG. Set to 1 to indicate that a mark display status exists. This will lock out normal displays.
5	15	DSKYFLAG. Bit set 1 when any keycode input is received from either DSKY, and not subsequently reset 0 (barring another fresh start). If bit is 0, display of quantities on DSKY lights is suppressed, leaving all DSKY lights blank. Bit is not set to 1 by an uplink input.
5	14	Not used.
5	13	Not used.
5	12	V59FLAG. Bit set 1 at the start of P23 in conjunction with initiation of a V59 display. Reset 0 if a proceed or enter response is received. If a mark is made a special display job is set up to display the calibration data at MARKDISP in R57 using a V06N87. After display of V06N87, V59FLAG is reset to prevent display from recurring.
5	11	INCORFLG. Bit set 1 in R22 (performed for P20) and P22 to indicate that computation pertinent to the first incorporation of observation data from a certain optics mark is being made. After this data has been incorporated in the state vector, bit is set 0 and a second incorporation is made.
5	10	PRFTRKAT. Preferred attitude flag. Defines to which attitude the spacecraft is to be aligned by R61. Set 1 by turn on of P20 or V76E. Reset 0 by V77E. A 1 means preferred tracking attitude. A 0 means X-axis attitude.
5	9	DMENFLG. Bit set 0 at the start of processing of optics mark data from a given object in P22 to indicate that r_1, W_6, W_7, W_8 have not been computed yet; bit set 1 after computation of these items. Bit also set 0 at the start of R22 (of P20).
5	8	COMPUTER. Bit set 1 as part of a fresh start and not subsequently changed, hence should remain at 1. Indicates that computations are being performed by CSM computer (as contrasted with LM computer), for use in those routines otherwise identical between the two computers. It is in erasable memory to permit the interpretive language bit-sensing orders to be used.

Flagword	Bit	Meaning
5	7	ENGONFLG. Bit set 1 just before the SPS engine is turned on (Bit 13 of channel 11 set 1), and reset to 0 just before the engine is turned off (bit 13 of channel 11 set 0). Used in the event of a restart to determine the proper setting for the engine-on channel bit (bit 13 of channel 11); if set 1 engine should be on.
5	6	3AXISFLG. Bit set 1 prior to entering R60 if the attitude maneuver to be made is specified by 3 angles. If it is zero, another routine is performed to compute the required angles from information on the spacecraft axis to be pointed and the direction in which it is to be pointed. Bit is reset 0 before exit is made from R60. Bit set 1 for uses of attitude maneuver routine based on input of V49 for R62.
5	5	GRRBKFLG. Set 1 when a V75E is executed, to serve as a backup liftoff signal. Bit tested before and after gyro-compassing during each half second cycle of P02 and if bit is 1 or bit 5 of channel 30 is 0 (the prime liftoff signal input) then P11 is started. Same two bits also checked for control purposes by V43.
5	4	R60FLAG. When bit set 1 R61 will use R60 to perform attitude maneuver. When bit set 0 R61 will compute desired gimbal angles and determine whether R60 maneuver is necessary. Bit is set and reset in P20 initialization and P20 restart (P20 in background when targeting program is selected via V37). Tested in CRS 61.1.
5	3	SOLNSW. Set to 1 by the LAMBERT routine if the routine could not accurately solve the problem with which it was called (i.e. if sufficient convergence was not achieved to the specified transfer time, or if the subtended true anomaly difference between the two input position vectors was less than about 1/2 minute of arc). Reset to 0 by LAMBERT if a successful LAMBERT solution was obtained. Set to 1 by the TIME-RADIUS Routine if this routine was called with an orbit having an eccentricity less than about 0.000004, and reset to 0 if the eccentricity was greater than this value (regardless of what the specified terminal radius is, and regardless of whether this radius could be reached conically

Flagword	Bit	Meaning
5 (cont)	3	from the input state vector). Thus, for the TIME-RADIUS Routine, the resetting of this bit to 0 does not necessarily imply a successful TIME-RADIUS solution. This bit is never tested by any of the mission programs. This bit is equivalent to the switches f_5 and f_9 of Section 5.5 of this GSOP. These two switches are represented by the same bit in the AGC.
5	2	MGLVFLAG. Bit used by MIDGIM subroutine. Set 0 if middle gimbal angle of the active vehicle to the input delta velocity vector was computed. Set 1 if the input delta velocity vector was converted to local vertical coordinates of the active vehicle.
5	1	RENDWFLG. Bit set 1 if W-Matrix is considered valid for use in performing rendezvous navigation (using P20). Bit 6 of FLAGWRD3 is used for the analogous function with orbital navigation (P22). This bit is set to 1 in R22 after processing of a set of mark information has been started. Set 0 by orbital integration if W-Matrix integration overflows. Set 0 by V67 if new data entered in response to V06N99. Set 0 by P27 on state vector update. Set 0 by P22, P23. Tested in AVETOMID: if bit is 1 W-Matrix is integrated to PIPTIME using pre-thrust state vector. Also tested in P00 periodic integration: if 1 W-Matrix is integrated to CSM state vector time using LM state vector.
6	15	DAPBIT1. Bit used with bit 14 to indicate current status of DAP.
6	14	DAPBIT2. Bit used with bit 15 to indicate current status of DAP. Used to implement lockout of V46E and V48E inputs if TVC DAP is running, and to cause restart of RCS or TVC DAP as appropriate if a restart is encountered. Bits are set to 00_2 if a V46E is received (with bits not 10_2) and bits 14-13 of DAPDATR1 (loaded by R03) are 0, signifying that no DAP is desired, and are also set to 00_2 in P62 shortly after response to checklist code 00041_8. Bits are set to 01_2 when the RCS DAP is started (after TVC shutdown or after V46E, bits not 10_2, and bits 14-13 of DAPDATR1 unequal) or when RCS DAP computations resumed following a period of TVC DAP operation. Bits

Flagword	Bit	Meaning
6 (cont)	14	set to 00_2 at ignition; set to 10_2 0.4 seconds later (for TVC DAP indication). Bits set to 11_2 when Saturn Stick Function is called by V46E to indicate Saturn Stick control of T5.
6	13	Bit used for two distinct functions, hence assigned two separate mnemonics. ENTRYDSP. Set 1 in P62 after N61 responded to, and actuates the entry current display nouns when the entry exit code sequence is used (set 0 to suppress display). Set 0 in P65 before flashing display N69 is activated. Set 1 in P65 after N69 is responded to with a PROCEED. Set 1 at start of P67 if came from P65 with flashing display N69 still active. STRULLSW. A 1 indicates steering and time to engine cutoff computations should be permitted (STEERSW set 1) 2 seconds after ignition. When 0 STEERSW not touched. Cleared to 0 for the V97E response (R40) if re-ignition is for impulsive burn. Set 1 at ignition if non-impulsive burn (steering to be done). Cleared to 0 at re-ignition for impulsive burn.
6	12	CMDAPARM. Bit set to 1 to "arm" the entry DAP (to allow "entry firings and calculations"). Bit is set to 1 in P62 shortly after bit 11 of this word becomes 1 (with 1/2 second), having previously been set 0 in P62 shortly before start of 00041_8 checklist display. If bit is 0, entry DAP computations are halted after computation of vehicle body rates.
6	11	GAMDIFSW. Bit set to 1 to permit initialization of entry DAP computations to proceed (see bit 12 of this word), and to permit an entry DAP quantity to be computed as the first difference of the present and previous values of a cell. Bit set to 0 in P62 shortly before start of 00041_8 checklist display, and set to 1 within 2 seconds (the first Average-G cycle following).
6	10	GONEPAST. Bit initialized to 1 near the start of P63 to prevent lateral control before D >.05g. Switch set 0 when .05g sensed (c.f. INRLSW) and subsequently set to 1 if in P67 bit 8 (GONEBY) of FLAGWRD7 is sensed as 1 (hence is a "latched" version of this bit 8). If this GONEPAST bit is 1, no lateral control computations are done, and the desired lift is set to maximum down (provided that g-limiter constraints are not violated).

Flagword	Bit	Meaning
6	9	RELVELSW. Bit initialized to 0 near the start of P63 and subsequently set to 1 if bit 8 of this word is 1 and the output of the Average-G equations indicates a velocity magnitude of less than about 12883.1 ft/s (causes, if 1, "earth-relative velocity" to be used for entry targeting and computations. Also set 0 near start of P61.
6	8	Bit used for three distinct functions, hence assigned three separate mnemonics. KNOWNFLG. Always 1 if earth is sphere of influence. Set as follows if moon is sphere of influence: Set to 1 in P22 if DSKY input indicates that landmark is known (octal digit #1 is odd in R2 for the V05N70 display), and set 0 in same routine if DSKY input indicates that landmark is "unknown" (octal digit #1 is even). EGSW. Bit initialized to 0 near the start of P63 and subsequently set to 1 when P67 is started (the "final phase" of the entry computations). Used by TARGETING for range prediction. R57FLAG. A 1 means do not do optics calibration. A 0 means do optics calibration. Set 0 or 1 and tested within P23.
6	7	NOSWITCH. Set 0 after start of P63. Set 1 during P65 if D > 140 ft/s/s, and prevents lateral reversal of roll command on that steering cycle. Unconditionally set 0 before terminating steering cycle.
6	6	HIND. Bit initialized to 0 near the start of P63 and subsequently set to 1 when some entry iteration calculations are to be performed. (For orbital entries velocity expected to be less than 27,000 ft/s, these calculations are not expected to be entered and hence bit expected to remain 0.
6	5	INRLSW. Bit initialized to 0 near the start of P63 and subsequently set to 1 the first time the sensed drag is 0.05g or more (a "latched" version of bit 3 of this word). For orbital cases, velocity is expected to be less than 27,000 ft/s, bit not subsequently sensed after becoming 1.

Flagword	Bit	Meaning
6	4	LATSW. Bit set to 1 in P62 shortly before start of 00041_8 checklist display, and also near the start of P63. Bit is set 0 by entry guidance computations to enforce a roll "over the top" by the entry DAP (which resets the bit to 1). For orbital cases, velocity is expected to be less than 27,000 ft/s and bit not expected to be set 0 since computations not entered.
6	3	Bit used for two distinct functions, hence assigned two separate mnemonics. .05GSW. Bit initialized to 0 in P62 shortly before start of 00041_8 checklist display, and also near the start of P63. Bit set to 0 when sensed drag in P64 becomes less than 0.05g and set to 1 when it is (P63 too) 0.05g or more. Bit used in entry DAP to control nature of computations which are performed. NTARGFLG. A 1 means astronaut did overwrite delta velocity. A 0 means astronaut did not overwrite delta velocity. Set to 0 in subroutine S34/35.5 (used by P34, P35, P74 and P75) initially before displaying Noun 81. Upon receipt of new data (recycle) for Noun 81, NTARGFLG is set to 1 before recycling to display the new data. Upon proceed response to Noun 81 when NTARGFLG has been set to 1 subroutine S34/35.3 is called to compute the new delta velocity in reference coordinates and the new target position.
6	2	CM/DSTBY. Bit set to 1 to indicate that entry DAP not to be in "standby" (i.e. that it is "activated"). Bit initialized to 1 in P62 shortly before start of 00041_8 checklist display, and reset to 0 in P67 after response to the V16N67 display when velocity has become less than 1000 ft/s. When entry DAP senses that bit is 0, channels 5 and 6 are set 0 and the 0.1-second cycling of the computations is terminated.
6	1	GYMDIFSW. Bit initialized to 0 in P62 shortly before start of 00041_8 checklist display, and subsequently set 1 in entry DAP if is 0 and bit 2 of this word is 1 and bit 6 of IMODES33, is 0. A value of 1 means that CDU differences and body rates can be computed (and therefore computations continued subject to other bits, such as bit 12 of this word).

Flagword	Bit	Meaning
6 (cont)	1	Bit is reset to 0 if bit 6 of IMODES33 is 1, and also in P67 after response to the V16N67 display (see bit 2 of this word).
7	15	TERMIFLG. Bit used in R52 (automatic optics positioning routine) in conjunction with P22 and P52 (i.e. not P20) for an analogous function: it is set 0 at start of routine, and set 1 in R53 after optics marks received.
7	14	ITSWICH. A 1 means a solution for TPI time has not yet been reached. A 0 means a solution for TPI time has been reached. Set to 1 at the beginning of P34 and P74, and then immediately set to 0 only if the TPI time is given and the elevation angle is to be computed. Bit is tested at SWCHCLR: if 1 it is immediately set to 0 and control is transferred to INTLOOP where the final solution for TPI time is reached; if 0, then either the TPI time or the elevation angle is displayed depending on the setting of ETPIFLAG . ITSWICH also tested at TESTY: if 1 the program looking for a solution for TPI time; if 0 the computed elevation angle is stored.
7	13	IGNFLAG. Cleared by V37 logic - viz. for P40. Set 1 by TIG-0 to indicate that nominal ignition time has arrived. Note, if TIG-0 finds ASTNFLAG set 1 (crew has OK'd ignition) then ignition is immediate; otherwise ignition waits for receipt of the PROCEED response to the TIG-5 flashing V99 (please enable engine) display. Set 1 (redundantly) by the ENTER response to the flashing V97 (perform engine fail procedure) display. Note, since IGNFLAG is set 1, not cleared, by the "recycle for re-ignition" V97 ENTER response, ignition will be immediate upon receipt of the PROCEED response to the subsequent flashing V99 display.
7	12	ASTNFLAG. Cleared by V37 logic - viz. for P40. Set 1 by the PROCEED response to the TIG-5 flashing V99 (please enable engine) display. Note, if V99P logic finds IGNFLAG set 1 (nominal ignition time has passed) then ignition is set up immediately, otherwise ignition waits for TIG-0. Cleared also by the ENTER response to the flashing V97 (perform engine fail procedure) display, forcing re-ignition delay until receipt of the PROCEED response to the subsequent flashing V99 display.

Flagword	Bit	Meaning
7	11	TIMRFLAG. Bit set to 1 to permit a self-perpetuating waitlist task to continue, which loads time-to-go with the difference between T_{now} and T_{ig}. The time-to-go cell is displayed automatically by the program for nouns 35, 40, 45, 59, and 99, and hence the bit is 1 while one of these nouns is being displayed (the "time" generally is from nominal ignition or predicted cutoff).
7	10	NORMSW. Set to 1 to specify to the LAMBERT routine that it is to use the unit normal vector (to the conic transfer plane) which is provided by the calling program; reset to 0 if LAMBERT is to calculate its own unit normal vector (by crossing the initial and final position vectors of the transfer). Set to 1 by the Initial Velocity Routine, INITVEL (the only routine which calls LAMBERT) whenever INITVEL is called with a (true or offset) target vector which lies inside "the cone"; reset to 0 by INITVEL whenever INITVEL is called with a (true or offset) target vector which lies outside "the cone". ("The cone" is a mathematically - defined cone whose vertex is the origin of coordinates, whose axis is the 180° transfer direction, and whose semi-cone angle is specified to INITVEL.) The semi-cone angle is set to 15° by P34, P35, P38, P39, P74, P75, P78, and P79, because active vehicle transfer angles between 165° and 195° are normally avoided in the targeting procedure. However, if a transfer angle falling within this $180^{\circ} \pm 15^{\circ}$ sector is intentionally selected by any one of the above targeting programs, or by the results from any one of the above maneuver program during an intercept trajectory targeted for more than 180°, the Lambert Aim Point Maneuver Prethrust Routine increases the semi-cone angle to 45° so that active vehicle transfer angle will not change from inside to outside the cone angle during the powered maneuver. Such a condition is undesirable since the intercept trajectory would be retargeted during the powered maneuver. Likewise, if the initial transfer central angle falls outside the 15° semi-cone angle, the semi-cone angle is decreased to 10° to reduce the possibility of a transfer angle changing from outside to inside the cone during a powered maneuver. NORMSW

Flagword	Bit	Meaning
7 (cont)	10	is set to 0 by P31 and P37 because the semi-cone angle should be set to 10^{o} for these programs. NORMSW should generally remain 0, unless transfers between 165^{o} and 195^{o} are intended. NORMSW is equivalent to the switch f_2 of section 5.5, and to the switch S_R of section 5.3.3 of this GSOP.
7	9	RVSW. Set to 1 to indicate to the TIME-THETA and TIME-RADIUS Routines that the only desired output is the time required to transfer through the specified transfer angle or to the specified radius respectively, and set to 0 to indicate that the state vector at the terminal point is desired in addition to the transfer time. Set to 1 during the course of the computations of the CM Lunar Landmark Selection Program, the Pre-TPI Maneuver Programs P34 and P74, the Pre-TPM Maneuver Programs P35 and P75, and the Stable Orbit Rendezvous Midcourse Programs P39 and P79. Set to both 0 and 1 by the Return to Earth Maneuver Program P37. The bit is equivalent to the inverse of the switch f_6 of Section 5.5 of this GSOP.
7	8	GONEBY. Bit set 0 each time through the entry "targeting" routine (entered every 2 seconds after Average-G is performed, starting about 2 seconds after the beginning of P63 and ending after a response to the V16N67 display in P67 (velocity below 1000ft/s)). Bit is then set 1 again if it is concluded that the vehicle has passed (i.e. overshot) the target. Bit is used to determine the sign (minus if bit 0, otherwise plus) of the R3 display for noun 64 and the R1 display for noun 67, and is also used to determine if bit 10 of flagword 6 should be set: mechanization permits a new sign to be determined each computing interval.
7	7	Not used.
7	6	V37FLAG. Bit set 1 at the same time that bit 1 of FLAGWRD1 is set 1, i.e. when Average-G is "started", and set 0 when the Average-G state vector has been loaded into the orbital integration state vector cells (at the conclusion of the last Average-G cycle, which found bit 1 FLAGWRD1 equal to 0 as a result of V37 action). Consequently, bit would be expected to be set to 0 within about 2 seconds of the time that bit 1 of FLAGWRD1 is set 0.

Flagword	Bit	Meaning
7	5	Not used.
7	4	UPLOCKFL. Set to 1 if failure of the $\overline{kkk}$ data check is detected in processing an input from the uplink receiver. The bit can be reset by sending an error reset code via the uplink (the DSKY error reset key does not reset the bit). While the bit is 1, all uplink information except an error reset code is rejected by the program.
7	3	VERIFLAG. Bit whose value is complemented when the final proceed entry is received in P27, indicating that the uplink information is to be used.
7	2	ATTCHFLG. Bit set 1 if bits 14-13 of DAPDATR1 are 10_2 when R03 is performed or when the RCS DAP is started (e.g. as a result of V46E or after TVC DAP completion). The bit being 1 means that LM is attached (otherwise, bit is set 0); bit not otherwise sensed in program.
7	1	TFFSW. Bit set 1 if perigee time is to be calculated, and set 0 if TFF (to a specified interface altitude) is to be computed. When R30 is performed via V82E (every 2 seconds if Average-G is on and on a single-shot basis otherwise) bit is set 1 if perigee altitude at least 300,000 ft above pad radius for earth coordinates or 35,000 ft above lunar landing site for moon coordinates and then is set 0 for calculation of TFF. Hence bit would generally be observed as 0.
8	15	RPQFLAG. Internal flag in integration to indicate if primary body to secondary body position vector (RPQ) was computed; a 0 indicates RPQ was computed, a 1 indicates RPQ was not computed. RPQ is computed only when MIDFLAG is set 1.
8	14	Not used.
8	13	NEWIFLG. Internal flag in integration. Used to engage 4 time step only on the first step of P00 integration; 1 means first step, 0 means not first step.

Flagword	Bit	Meaning
8	12	CMOONFLG. Indicates origin of "permanent" CSM State Vector; 1 means lunar-centered, 0 means earth-centered. Always set to 0 or 1 depending on MOONFLAG when permanently updating the CSM state vector. Set to 0 in fresh start.
8	11	LMOONFLG. Indicates origin of "permanent" LM State Vector; 1 means lunar-centered, 0 means earth-centered. Always set to 0 or 1 depending on MOONFLAG when permanently updating the LM state vector. Set to 0 in fresh start.
8	10	ADVTRK. A 1 means use auto optics to drive optics to a LMK on advanced ground track. A 0 means use auto optics to drive to star, LM or landmark. Set 1 when entering auto optics via ADVORB (advanced orbit). Set 0 when entering auto optics via R52. Tested in each computational cycle of auto optics.
8	9	P39/79 SW. A 1 means P39/P79 operating. A 0 means P38/P78 operating. Bit set 1 when P39 or P79 is selected. Set 0 when P38 or P78 is selected. Bit tested in code shared by P38/P78, P39/P79 to determine points of return upon execution completion.
8	8	SURFFLAG. Indicates whether LM is on lunar surface. Set and reset manually with extended verbs 44 and 45 respectively. Tested in P00 periodic integration and if set, LM state vector is not integrated. Also tested in orbital integration and if set, the planetary inertial orientation routine is used to transform RLS to reference coordinate system. Lunar velocity is also computed in reference coordinate system.
8	7	INFINFLG. Set to 1 in the conic TIME-THETA Routine to indicate that the routine was called with a hyperbolic initial state vector and a true anomaly transfer angle which was so large as to require a transfer past the hyperbolic asymptote of the conic, which is physically impossible. Set to 0 in TIME-THETA if a valid physical solution is obtained. Set to 1 in the conic TIME-RADIUS Routine to indicate that the routine was called with a hyperbolic initial state vector, a desired final radius,

Flagword	Bit	Meaning
8 (cont)	7	and a desired sign of the radial velocity of the final radius (to indicate whether trajectory is to be inbound or outbound here) which would require a transfer past the hyperbolic asymptote of the conic. For example, a spacecraft which is inbound can never return inbound to a radius which is greater than its current radius, and likewise a spacecraft which is outbound can never return outbound to a radius which is less than its current radius. Set to 0 in TIME-RADIUS if a valid physical solution is obtained. Set to 1 during any one (or several) of the internal LAMBERT iterations if the intermediate solution arrived at on this particular internal iteration required a transfer past a hyperbolic asymptote. The LAMBERT routine senses such a situation on the succeeding iteration and adjusts various parameters in an attempt to obtain a valid solution. Set to 0 in LAMBERT if the preceding internal iteration yielded a physically realizable transfer. The bit is never tested or set either way outside the conic subroutines. The bit is equivalent to the switch f_7 of Section 5.5 of this GSOP.
8	6	ORDERSW. Never set to 1. Set to 0 as part of a fresh start. Used to control the type of computation performed in the ITERATOR routine (part of the conic subroutines). This bit is equivalent to the switch f_4 of Section 5.5 of this GSOP.
8	5	APSESW. Set to 1 by the TIME-RADIUS routine to indicate that the routine solved for the time required to reach pericenter (or apocenter) rather than the desired radius, because the desired radius input to the routine was less than the pericenter radius (or was greater than the apocenter radius, respectively). Set to 0 by the TIME-RADIUS routine to indicate that the routine attempted to solve for the time required to reach the desired radius, since the desired radius input was greater than pericenter radius and less than apocenter radius. (Such a solution will be reached unless INFINFLG is set to 1). This bit is equivalent to the switch f_8 in Section 5.5 of this GSOP.

Flagword	Bit	Meaning
8	4	COGAFLAG. Set to 1 by the TIME-THETA routine and the TIME-RADIUS routine if either of these routines was called with an initial state vector having a flight-path-angle (measured from local vertical) less than 1^{0} 47.5' or greater than 178^{0} 12.5'. Set to 0 in each of these routines if either was called with an initial state vector having a flight-path-angle between these two extremes. The bit is not tested or set either way outside the conic routines, except that it is tested once in the CM Lunar Landmark Selection Program R-35.
8	3	Not used.
8	2	Not used.
8	1	360SW. Used to indicate the type of computation to be performed by the Universal Variable Routine (a subroutine called by the LAMBERT, TIME-THETA, and TIME-RADIUS routines). The bit is not of interest outside these three conic routines and in fact is neither tested nor set either way outside the Universal Variable Routine itself. The bit is equivalent to the switch f_{w} of Fig. 5.10-4 of Section 5.5 of this GSOP.
9	15	SWTOVER. A 1 indicates switchover has occurred. A 0 indicates switchover has not yet occurred. Set 1 by SWTCHOVR nominally 3.4 (CSM) or 6.4 (CSM/LM) seconds after ignition to indicate switchover has occurred. Set 0 by V37. Tested by BESTTRIM at SPS shutdown to determine which way trim estimates for next burn should be selected: pre-switchover (0) use the DELFILTER values; post-switchover (1) leave the trim estimates as they are.
9	14	V67FLAG. Set 0 whenever an extended verb V67 is taken. This verb displays the RMS position and velocity errors from the W matrix using a V06N99. If the astronaut then changes these values the bit is set 1. The bit is tested in the V67CALL routine: a 1 means compute new initial W-Matrix values for either rendezvous, orbital, or cislunar navigation; a 0 means do not compute these values.

Flagword	Bit	Meaning
9	13	V82EMFLG. A 1 indicates moon vicinity. A 0 indicates earth vicinity. Set 1 or 0 by R30 according to whether state vectors are moon- or earth-centered. Bit tested by SR30.1 when called by R30 to compute PERIGEE, APOGEE radius and PERIGEE, APOGEE height above launch pad or lunar landing site.
9	12	MAXDBFLG. A 1 indicates maximum RCS DAP deadband (5^{o}). A 0 indicates minimum RCS DAP deadband (0.5^{o}). Set 0 by SETMINDB called by P40 just prior to attitude maneuver R60, and again just prior to manual VG-trim operations after TVC burn. Also set 0 by SETMINDB called by P41 just prior to attitude maneuver. Set 1 by SETMAXDB called by P40 2.5 seconds after shutdown so that RCS is brought up in wide DB to conserve fuel. Set to 1 or 0 by exiting V37 logic (see below) and by extended verb V48 (R03) in response to DAPDATR1 (R1 of N46). Tested by V37 and recorded so V37 at exit from the program can set it back to the original value.
9	11	V94FLAG. A 1 indicates Extended Verb 94 is allowed. A 0 indicates Extended Verb 94 not allowed. Set 1 before P23 enters R52 so astronaut may re-maneuver spacecraft LLOS before marking. Set 0 after mark so spacecraft does not re-maneuver after that time. Tested at VERB94.
9	10	SAVECFLG. A 1 means P23 display code used and data stored after mark is done. A 0 means P23 display code used and data stored before mark is done. Used in unpacking of N70/N71.
9	9	VHFRFLAG. A 1 allows R22 to accept range data. A 0 stops acceptance of range data. Set 1 by Verb 87. Set 0 by Verb 88. Tested each time a mark is processed by R22.
9	8	SOURCFLG. A 1 indicates source of input data is VHF radar. A 0 indicates source is optics mark. Set 1 when a VHF radar mark is processed. Set 0 when an optics mark is processed. Tested each time a mark is processed by R22.
9	7	Not used.

Flagword	Bit	Meaning
9	6	N22ORN17. Bit set 1 means use the angles stored in N22 to compute the "total attitude error" for display on FDAI error needles. Bit set 0 means use the angles stored in N17. Set 1 by Verb 62. Set 0 by Verb 63. Set o by fresh start. During normal RCS DAP operation if bit 9 of flagword 0 is set (i.e. display "total attitude errors") the bit N22ORN17 is checked every other pass thru Phase 1 of the RCS DAP.
9	5	QUITFLAG. Set to 1 by extended Verb 96 (which then exits to P00) to indicate that integration should be discontinued. Bit is examined by integration routines which exit if the bit is 1. Reset to 0 in P00 if it was found to be 1. Integration is disabled until a new program (other than P27) is selected.
9	4	R31FLAG. Bit set 1 at V83PERF in response to V83 to indicate R31 is selected for operation. Bit set 0 at V85PERF to indicate R34 is selected for operation. Tested in R31/R34 to determine formulation of angle RTHETA: if R31FLAG is 1 then angle Theta is computed as the angle between X-body axis and the local horizontal; if R31FLAG is 0 then angle Phi is computed as the angle between SXT LOS and local horizontal.
9	3	MID1FLAG. Bit set 1 to indicate that MIDTOAV1 called integration.
9	2	MIDAVFLG. Bit set 1 to indicate that integration was called by MIDTOAV1 or MIDTOAV2 (R41). Bit set 1 engages R41 logic.
9	1	AVEMIDSW. Set to 1 to indicate that synchronization of state vectors and W-Matrix is in progress in the transition from powered flight to coasting flight and that the powered flight state vector should not be overwritten until the synchronization is completed.

Word Number	Contents
45-50a	DSPTABs. The eleven registers, DSPTAB through DSPTAB+10D, indicate the status of the DSKY displays. If bits 15 through 12 are 0001, the next 11 bits will indicate the actual status of the DSKY displays; if bits 15 though 12 are 1110, the next 11 bits indicate the "ones" complement of the status to which the CMC will command the DSKY display. Bits 11-1 of DSPTAB+0 through DSPTAB+10D are decoded as follows:

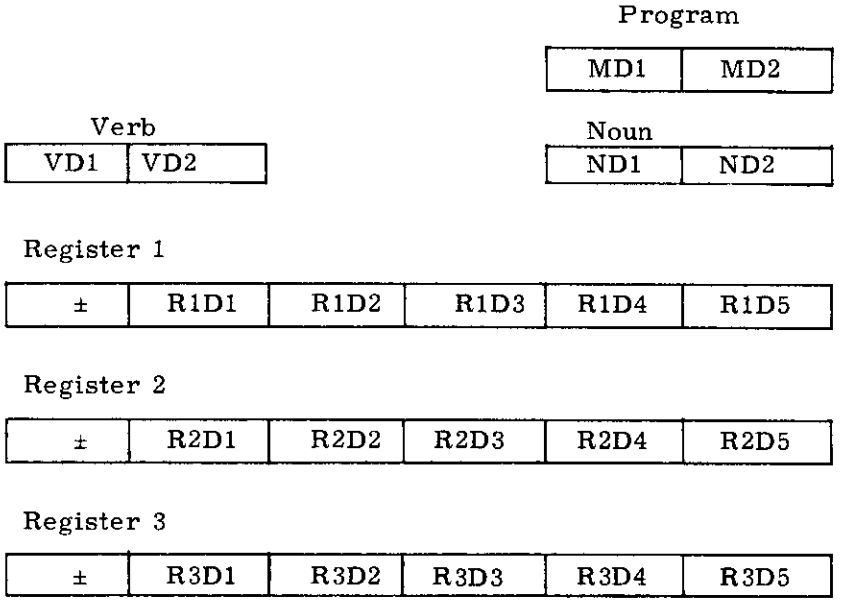
DSPTAB Register	Downlink Word Number	Bit Assignments		
		Bit 11	Bits 10-6	Bits 5-1
DSPTAB+0	45a	-R3S	R3D4	R3D5
DSPTAB+1	45b	+R3S	R3D2	R3D3
DSPTAB+2	46a		R2D5	R3D1
DSPTAB+3	46b	-R2S	R2D3	R2D4
DSPTAB+4	47a	+R2S	R2D1	R2D2
DSPTAB+5	47b	-R1S	R1D4	R1D5
DSPTAB+6	48a	+R1S	R1D2	R1D3
DSPTAB+7	48b			R1D1
DSPTAB+8D	49a		ND1	ND2
DSPTAB+9D	49b		VD1	VD2
DSPTAB+10D	50a		MD1	MD2

R3D1 stands for digit one of the third register and VD1 stands for the first digit of the verb display, etc. For the right character of a pair, bit 5 is the MSB with bit 1 the LSB. For the left character of a pair, the MSB is bit 10 with bit 6 the LSB. Bit 11 of some of the DSPTABs contains discrete information, a one indicating that the discrete is on. For example, a one in bit 11 of DSPTAB+1 indicates that R3 has a plus sign. If the sign bits associated with a given register are both zeros, then the content of that particular register is octal; if either of the bits is set, the register content is decimal data.

Word Number	Contents
45-50a (cont)	The five bit codes associated with the digits are as follows:

	MSB				LSB
0	1	0	1	0	1
1	0	0	0	1	1
2	1	1	0	0	1
3	1	1	0	1	1
4	0	1	1	1	1
5	1	1	1	1	0
6	1	1	1	0	0
7	1	0	0	1	1
8	1	1	1	0	1
9	1	1	1	1	1
Blank	0	0	0	0	0

The following is a diagram of the DSKY face showing positions of the different digits:



Word Number	Contents
50b	DSPTAB+11D. This register drives relays for display lights. The bit assignments are:

Bit	Assignment
1	
2	
3	
4	No Attitude
5	
6	Gimbal Lock
7	
8	Tracker
9	Program Caution
10	
11	

If bits 15 through 12 of DSPTAB+11D are 1000, the last 11 bits indicate the state to which the CMC will command the relays; if bits 15 through 12 are 0000, the last 11 bits indicate the actual state of the relays. A one indicates that the discrete is on.

51 TIME2, TIME1. A double precision word indicating ground elapsed time. Used for all timing while the CMC is on. Zeroed at liftoff and incremented by one bit per centisecond. It may be updated by Extended Verb 55 (R33) or by Extended Verb 73 (P27). Scaled centiseconds/2^{28}.

52-58 LM STATE VECTOR AND TIME. The CMC's latest calculated state vector for the LM in either earth-centered or moon-centered reference coordinates. A zero in bit 11 of flagword 8 (LMOONFLG) indicates earth-centered whereas a one indicates moon-centered. Words 52-54 contain the position coordinates, X, Y, and Z, scaled meters/2^{29}. Words 55-57 contain the velocity components, X, Y, and Z, scaled (meters/centisecond)/2^{7}. Word 58 contains the time associated with the LM state vector in words 52-57, scaled centiseconds/2^{28}. These parameters are calculated whenever the LM state vector is permanently extrapolated or changed, as follows:

P00 - every 10 mins. to CM state vector time.
P20 - every mark and every Incorp if LM connected.
P27 - update of state vector
R32 and V66.

Word Number		Contents	
(Cont.)	90a	Bit	Meaning
	(Cont.)	15	(Temperature caution) of channel 11 is set to agree with this bit. Bit set 0 for a fresh start or restart.
		14	Last sampled value of channel 30 bit 14 (0 if ISS has been turned on or commanded to be turned on). Bit set 1 for a fresh start or restart, thereby causing IMU CDU's to be zeroed.
		13	Last sampled value of channel 30 bit 13 (0 if an IMU fail indication produced). Set 1 for a fresh start or restart; if bit becomes 0 while bit 4 of this word is also zero, then channel 11 bit 1 (ISS Warning) is set 1.
		12	Last sampled value of channel 30 bit 12 (0 if an IMU CDU fail indication produced). Set 1 for a fresh start or restart; if bit becomes 0 while bit 3 of this word is also zero, then channel 11 bit 1 (ISS Warning) is set 1.
		11	Last sampled value of channel 30 bit 11 (0 if an IMU cage command produced by crew). Set 1 for a fresh start or restart.
		10	Last sampled value of channel 33 bit 13 (0 if a PIPA fail indication produced), having same value as bit 13 of IMODES33. Bit is set 1 for a fresh start or restart, and if an error reset key code is received via DSKY or uplink. If bit becomes 0 while bit 1 of this word is also zero, then channel 11 bit 1 (ISS Warning) is set 1.
		9	Last sampled value of channel 30 bit 9 (0 if IMU turned on and operating with no malfunctions). Set 1 for a fresh start and set to 0 for restart. Alarm 0214_8 is generated if bit goes from 0 to 1 while bit 8 (IMUSE) of Flagword 0 is 1.
		8	Bit used to control the IMU turn-on sequencing. It is set 1 if bit 7 of this word is sensed as 1, and is reset (with bit 7) to zero 0.48 secs later, before starting the IMU turn-on sequencing. Used to acheive a wait of 0.48 secs before acting on the IMU turn-on information. Set 0 by fresh start or restart.

Word Number	Contents
75	CENTRAL ANGLE. The angle traversed by the passive vehicle between TPI time (TTPI) and intercept time (TPASS4), scaled degrees/360. This item can be computed by the TPI Search program or inputted via the DSKY and it is used in computing the time of flight (TPASS4-TTPI). It is calculated once during each pass through P17 (TPI Search).
76	OFFSET POINT. The desired distance between the CSM and LM measured along the orbit of the passive vehicle and scaled, meters/2^{29}. This quantity is never calculated but is always used as an input, via the DSKY, to the Stable Orbit program (P38/P78) and used in determining the target vector for Lambert.
77	TWO FLAGWORDS (10, 11). Bit assignments are as follows:

Flagword	Bit	Meaning
10	15	Not used.
10	14	INTFLAG. A 1 indicates that some program or routine has called INTSTALL and is presumably in the process of integrating. Other programs calling INTSTALL will wait until this bit is reset to 0. A 0 indicates that no program or routine is currently using integration. Set 1 by INTSTALL. Set 0 by INTWAKE. A hardware or software restart sets this bit to 0.
10	13	Not used.
10	12	Not used.
10	11	Not used.
10	10	Not used.
10	9	Not used.
10	8	Not used.
10	7	REINTFLG. A 1 indicates that the routine currently using INTSTALL is to be restarted. A 0 indicates that no restartable integration is in progress. Programs which have restart points during integration set this bit to 1. INTWAKE sets this bit to 0. Bit is untouched by hardware and software restarts thus retaining INTSTALL for restartable programs.

Flagword	Bit	Meaning
10	6	Not used.
10	5	Not used.
10	4	Not used.
10	3	Not used.
10	2	Not used.
10	1	Not used.
11	15	Not used.
11	14	Not used.
11	13	Not used.
11	12	Not used.
11	11	Not used
11	10	Not used.
11	9	Not used.
11	8	Not used.
11	7	Not used.
11	6	Not used.
11	5	Not used.
11	4	Not used.
11	3	Not used.
11	2	Not used.
11	1	Not used.

Word Number	Contents
78	TEVENT. The time of liftoff (P11, clock zeroing) or time of any SPS ignition or shutdown (P40), whichever occurs last. It is scaled centiseconds/2^{28} and referenced to the computer clock. In P11, for the space of eight instructions (approx. 17 MCT), the 2 OCT value (7776400013) is stored in TLIFTOFF/TEVENT for P11 restart protection. The correct TIME2/TIME1 then overwrites the 2 OCT constant.
79	Repeat of word 29 of this downlist.

Word Number	Contents
80a	OPTMODES, a cell whose individual bits are used to control the performance of optics functions within the "T4RUPT" package. Set to 00130_8 (bits 7, 5, 4 = 1) as part of a fresh start; a restart preserves the present values of the bits 9, 5, 4, while setting bit 7 to 1 and zeroing the remaining bits (15-10, 8, 6, 3-1). Word is updated once every 0.48 seconds, about 0.12 seconds before the interrupt that updates IMODES30 & IMODES33.

Bits	Meaning
15-11	Not assigned, hence expected to remain 0.
10	Bit set 1 to indicate that zeroing of optics completed since last fresh start or restart (both of which set the bit 0). If an attempt is made to drive the optics and this bit is found to be zero, alarm 0120_8 is generated (but computation proceeds).
9	Bit set 1 if optics switched from computer control mode (while being driven, i.e. "coarse aligned") to another mode. Value used when switch back to computer control mode to re-enable driving. Bit set 0 as part of fresh start and when optics system released (at end of marking); a restart preserves the bit (see, however, bit 10).
8	Not assigned, hence expected to remain 0.
7	Last sampled value of channel 30 bit 7 (0 if an optics CDU fail indication has been generated by the optics CDU hardware). If bit 2 of this word is 0, a Tracker alarm (bit 8 of DSPTAB+11) is generated if this bit has a 1 to 0 transition. Bit set 1 by a fresh start or restart.
6	Not assigned, hence expected to remain 0.
5	Last sampled value of channel 33 bit 5 (0 if optics mode switch set to computer control).
4	Last sampled value of channel 33 bit 4 (0 if optics mode switch set to zero optics). If bits 5-4 = 11_2, this means that optics mode switch set to manual mode.
3	Bit set 1 when optics mode switch changed from manual or computer control mode to zero optics mode, to indicate that zeroing of the optics is in progress.

Word Number	Bits	Contents Meaning
(Cont.) 80a	(Cont.) 3	If bit is 1 and bit 1 of this word is 0, then a switch out of zero optics mode will cause alarm 0116_8 to be generated (if switched to manual, a "grace period" of about 5.3 seconds is provided before the optics-zeroing time counter is reset, during which time a switch back to optics zeroing can be made). Bit remains 1 for about 16.2 seconds, and is then reset to 0(at same time that bit 10 of this word is set 1, and bits 2-1 of this word set 0).
	2	Bit set 1 to inhibit generation of Tracker alarm (bit 8 of DSPTAB+11) if bit 7 of this word goes from 1 to 0. Bit set 1 at the same time as bit 3, and reset 0 at end of wait (again at the same time as bit 3). This bit does not affect the setting of bit 8 of DSPTAB+11 due to excessive IMU CDU change after an optics mark (which also produces alarm 0121_8).
	1	Bit set 1 to indicate that end of optics zeroing delay will occur in 0.4 seconds (remains 1 for that length of time, and then is reset to 0 at the same time as bits 3-2). If bit is 1, generation of alarm 0116_8 (see bit 3) is inhibited. Since updating of other bits (i.e. bit 5-4) of this word done only once every 0.48 seconds, this bit has negligible effect on program performance (since start of 0.4 second period is the same as one of the 0.48 second samples).
80b		HOLDFLAG. A multiple purpose switch which is used for establishing the control reference of the autopilot. It has the following three states: State — Meaning (+) Sample the CDU angles and store in THETADX, THETADY, and THETADZ before resuming attitude hold and resetting HOLDFLAG to (+0). (+0) Remain in attitude hold about previously established reference angles, THETADX, THETADY and THETADZ. (-) Enable automatic steering.
81a		LEMMASS. The current mass of the LM vehicle, scaled kilograms/2^{16}. This is a pad load erasable and is not changed in normal use. The astronaut can change it, however, as part of the normal DAPDATA LOAD (R03, V48).

Word Number	Contents
81b	CSMMASS. The current weight of the CSM vehicle, scaled kilograms/2^{16}. It is a pad load erasable which can be altered by the astronaut in R03 (V48). It is changed automatically every 10 seconds during TVC by TVCEXECUTIVE. This change consists of decrementing the parameter by 290 kg. (638 lbs).
82	DAPDATR1, DAPDATR2. Information concerning the RCS-CSM DAP interfaces:

DAPDATR1 is packed with 5 octal digits of information as follows:

Bits	15-13	12-10	9-7	6-4	3-1
	CONFIG	XTAC	XTBD	DB	RATE

(1) CONFIG: Configuration
- 0 No DAP or ENTRY DAP
- 1 CSM
- 2 CSM/LM
- 3 CSM/SIVB
- 6 CSM/LM ASCENT STAGE ONLY

(2) XTAC: X-translation using Quads AC
- 0 No AC
- 1 Use AC

(3) XTBD: X-translation using Quads BD
- 0 No BD
- 1 Use BD

(4) DB: Deadband
- 0 ±0.5 degree
- 1 ±5.0 degrees

(5) RATE: Response to RHC, Automatic maneuvers
- 0 0.05 degree/second
- 1 0.2 degree/ second
- 2 0.5 degree/second
- 3 4.0 degrees/second

DAPDATR2 is packed with 5 octal digits of information as follows:

Bits	15-13	12-10	9-7	6-4	3-1
	AC-Roll	Quad A	Quad B	Quad C	Quad D

Word Number		Contents
(Cont.)	82	(1) AC-Roll: Roll jet selection 0 Use BD Roll 1 Use AC Roll (2) A, B, C, D Quad fails 0 Quad Failed 1 Quad OK
	83, 84a	ERRORX, ERRORY, ERRORZ. The RCS DAP phase plane (roll, pitch, yaw) attitude errors scaled degrees/180. During steady state operation the magnitude of ERRORX, Y, and Z should be less than the attitude deadband, ADB, (either 0.5 deg. or 5 deg.). When the CMC mode switch is in AUTO or HOLD, a magnitude greater than the ADB which exists for long intervals without diminishing at the rate as specified in DAPDATR1 would be an indication of bad RCS DAP performance. The RCS control axes, with which these errors are concerned, are rotated, with respect to the body axes, by -7.25 degrees about the +X axis. The error values are calculated: 1. During RCS DAP operation with CMC MODE switch in AUTO or HOLD, every 100 millisecs. 2. During RCS DAP operation with CMC MODE switch in FREE - not updated.
	84b	Garbage. THETADX, which is described in word 16a of the Powered Downlist will appear here.
	85-87	WBODYs or OMEGACs (when TVC DAP is on). WBODYs are the desired angular body rates (roll, pitch, yaw) about the control axes when RCS DAP is on, scaled (degrees/second)/450. The RCS DAP control axes are rotated w.r.t. body axes by -7.25 degrees about +X. OMEGACs are body axis rate commands in roll, pitch and yaw generated by cross-product steering (Roll is ignored by TVC). Bits 15 and 14 of Flagword 6, bits 15, 14 and 13 of DAPDATR1, and bit 15 of Flagword 9 indicate which parameter is being sent and the correct scaling for OMEGAC.

[X] Revised
[ ] Added GSOP # R-577 PCR # 237 Rev. 2 Date 8/1/68

Word Number	Contents			
(Cont.) 85-87	Bits 15, 14 Flagword 6	Bits 15, 14, 13 DAPDATR1	Bit 9 Flagword 9	
	01	XXX	X	WBODYS
	10	001	X	OMEGACS for CSM alone scaled (rev/sec)/12.5
	10	010 110	0	OMEGAC: for pre-switchover CSM/LM DAP. Scaled (rev/sec)/$\left(2^2 \frac{(\text{ETVCDT}/2)}{100}\right)^{-1}$ where ETVCDT/2 is pad-loaded erasable integer (1/2 the sample interval in centiseconds)
	10	010 110	1	OMEGACS for post-switchover CSM/LM DAP. Scaled (rev/sec)/6.25.

88a REDO COUNTER. Counter for hardware restarts. Set to zero by a keyboard fresh start (VERB 36). Incremented once per hardware restart by the restart program (GOPROG) and scaled 2^{-14}.

88b, 89 THETAD's. The final desired CDU angles, (X, Y, Z) treated as 15-bit unsigned quantities and scaled, degrees/360. THETAD+2 should not be in gimbal lock or near it. These items should not be confused with THETADX, Y, and Z.

90a IMODES30, a cell whose individual bits are used to control the monitoring of IMU functions associated with channel 30 (and in a few cases channel 33). Set to 37411_8 as part of a fresh start; a restart sets the word to 37400_8 plus the present contents of bits 5, 4, 3, 1 (zeroing bits 15, 8, 7, 6, and 2). Word is updated once every 0.48 seconds based upon the channel sampling controlled by the "T4RUPT" computations. Discussion below ignores settings performed by verb 35 ("lamp test").

Bit	Meaning
15	Last sampled value of channel 30 bit 15 (0 if IMU temperature within limits). If bit changes, bit 4

☐ Revised
☒ Added GSOP # R-577 PCR # 237 Rev. 2 Date 8/1/68

Word Number		Contents	
(Cont.)	90a	Bit	Meaning
	(Cont.)	15	(Temperature caution) of channel 11 is set to agree with this bit. Bit set 0 for a fresh start or restart.
		14	Last sampled value of channel 30 bit 14 (0 if ISS has been turned on or commanded to be turned on). Bit set 1 for a fresh start or restart, thereby causing IMU CDU's to be zeroed.
		13	Last sampled value of channel 30 bit 13 (0 if an IMU fail indication produced). Set 1 for a fresh start or restart; if bit becomes 0 while bit 4 of this word is also zero, then channel 11 bit 1 (ISS Warning) is set 1.
		12	Last sampled value of channel 30 bit 12 (0 if an IMU CDU fail indication produced). Set 1 for a fresh start or restart; if bit becomes 0 while bit 3 of this word is also zero, then channel 11 bit 1 (ISS Warning) is set 1.
		11	Last sampled value of channel 30 bit 11 (0 if an IMU cage command produced by crew). Set 1 for a fresh start or restart.
		10	Last sampled value of channel 33 bit 13 (0 if a PIPA fail indication produced), having same value as bit 13 of IMODES33. Bit is set 1 for a fresh start or restart, and if an error reset key code is received via DSKY or uplink. If bit becomes 0 while bit 1 of this word is also zero, then channel 11 bit 1 (ISS Warning) is set 1.
		9	Last sampled value of channel 30 bit 9 (0 if IMU turned on and operating with no malfunctions). Set 1 for a fresh start and set to 0 for restart. Alarm 0214_8 is generated if bit goes from 0 to 1 while bit 8 (IMUSE) of Flagword 0 is 1.
		8	Bit used to control the IMU turn-on sequencing. It is set 1 if bit 7 of this word is sensed as 1, and is reset (with bit 7) to zero 0.48 secs later, before starting the IMU turn-on sequencing. Used to acheive a wait of 0.48 secs before acting on the IMU turn-on information. Set 0 by fresh start or restart.

Word Number	Bit	Contents Meaning
(Cont.) 90a	7	Bit used to control the IMU turn-on sequencing. It is set to 1 based on logic using bits 14, 9, and 2 of this word, and is reset to zero (with bit 8 of this word) 0.48 secs later. Also set 0 by a fresh start or restart. Hence can be set to 1 if ISS initialization requested (bit 14 or bit 9 of this word changing) since last fresh start, turn-off of IMU (change in bit 9 of this word), or turn-on delay complete (changing in bit 14 of this word).
	6	Bit set 1 to indicate that IMU initialization is being carried out. Set 1 during turn-on sequence, if a cage command (bit 11 of this word) is received, or if IMU zeroing in "T4RUPT" is done (e.g. restart with IMU operating cf. bit 14 of this word). Set 0 by a fresh start or restart, about 10.24 seconds after removal of cage command, about 10.24 seconds after start of zeroing in "T4RUPT" (when bits 8-7 set 0), or about 94 seconds after start of turn-on sequence (when bits 8-7 set 0 marks the "start" of sequence). If bit is 1, no verb 37 input is processed (the two digits of the specified mode will be accepted, but then alarm pattern 1520_8 is generated). If bit is 1, an error exit from the internal IMU routines is forced (coarse align, fine align, or gyro torquing).
	5	Bit set 1 to inhibit the generation of program alarm 0212_8 if a PIPA fail signal (bit 13 of channel 33) is produced. Set 0 as part of a fresh start, and value retained if a restart. Bit not used unless bit 1 of this word is 1. Bit set to 1 during IMU turn-on sequence (when bit 6 is set 1), and reset 0 about 10.24 seconds after bit 6 is reset 0 (alarm generated when Average-G is stopped, if bit 10 of this word is 0, regardless of the value of this bit 5).
	4	Bit set 1 to inhibit generation of an ISS warning based on receipt of an IMU fail signal. Set 1 as part of a fresh start, and value retained if a restart. Bit reset to 0 when bit 6 is set 0 (having been set 1 when bit 6 set 1). Bit also set 1 when coarse align of IMU is started, and is set 0 about 5.12 seconds after mode change to fine align is done. Also set 1 for 10.24 seconds when IMU CDU zero commanded.

[X] Revised
[ ] Added GSOP # R-577 PCN# 585 PCR # ____ Rev. 2 Date 10/4/68

Word Number		Contents
(Cont.) 90a	Bit	Meaning
	3	Bit set 1 to inhibit generation of an ISS warning based on receipt of an IMU CDU fail signal. Bit set 0 as part of a fresh start, and value retained if a restart. Bit set 1 when bit 6 of this word set 1, and is set 0 (at end of IMU zeroing sequence) when bit 6 set 0. Bit also set 1 (at the same time as bit 4) for 10.24 seconds when IMU CDU zero is commanded separate from "T4RUPT" package (via V40 N20E).
	2	Bit set 1 to indicate failure of the turn-on delay sequence for IMU turn-on (alarm 0207_8 is also generated). Zeroed by fresh start or restart.
	1	Bit set 1 to inhibit generation of an ISS warning based on receipt of a PIPA fail signal (bit 13 of channel 33). Bit set 1 as part of a fresh start, and value retained if a restart. Bit also set 1 when bit 6 of this word is set 1 (but is not subsequently reset in the "T4RUPT" logic, cf. bit 5 of this word).
90b		IMODES33, a cell whose individual bits are used to control the monitoring of functions associated with channel 33 (and other items). Set to 16000_8 as part of a fresh start; a restart sets it to 16000_8 + the present contents of bit 6 (other bits set 0); and an error reset key code sets bits 13-11 to 1 (leaving other bits alone). Word is updated once every 0.48 seconds. Discussion below ignores settings performed by verb 35 ("lamp test") except for bit 1.
	Bit	Meaning
	15	Not assigned, hence expected to remain 0.
	14	Last sampled value of channel 32 bit 14 (0 if a Proceed command is given using the old "standby" button). A transition from 1 to 0 causes a job to be established that has same program logic effect as V33 E (from a mission program standpoint). Contrary to the other bits of this word, this bit is updated once every 0.12 seconds.

Word Number	Bit	Contents Meaning
(Cont.) 90b	13	Last sampled value of channel 33 bit 13 (0 if an accelerometer fail signal, or PIPA fail, produced by hardware). Same quantity loaded into bit 10 of IMODES30 (for program logic control convenience). Fresh start and restart bit set to 1.
	12	Last sampled value of channel 33 bit 12 (0 if a telemetry end pulse rejected because downlink rate too fast). When a 1 to 0 transition is sensed, alarm pattern 1105_8 is generated. Fresh start and restart set bit to 1.
	11	Last sampled value of channel 33 bit 11 (0 if an uplink bit rejected because uplink rate too fast). When a 1 to 0 transition is sensed, alarm pattern 1106_8 is generated. Fresh start and restart sets bit to 1.
	10-7	Not assigned, hence expected to remain 0.
	6	Bit set to 1 to indicate that IMU use for vehicle attitude information should not be attempted. Bit 1 the same time as bit 6 of IMODES30 is set1, and also when bit 4 of IMODES30 is set1 (for IMU zeroing external to "T4RUPT" and for IMU coarse align). Bit set 0 if IMU fine align routine is performed. Set 1 if IMU turned off.
	5	Bit set 1 in IMU zeroing routine external to "T4RUPT" while zeroing is taking place (for an interval of about 10.24 seconds, at the same time as bit 6 of this word is set in the routine). This routine is entered via V40 N20E. Program comments indicate that bit used "for ground" monitoring.
	4-3	Not assigned,hence expected to remain 0.
	2	Not assigned, hence expected to remain 0.
	1	Bit set to 1 when a verb 35 ("lamp test") is received, and reset to 0 about 5 seconds later. Used to inhibit resetting of lights to 0 in "T4RUPT"package while the lamp test is being performed.

Word Number	Contents
91-94	Channels 11, 12, 13, 14, 30, 31, 32, and 33. Bit assignments are as follows:

Word 91a, Channel 11. A computer output channel whose individual bits are used for display parameter quantities and engine on/off control. Set 0 by a fresh start. A restart or processing of a V37 program change causing the computer program number to be changed preserves the present value of bit 1 of the channel and sets remaining bits to 0. A restart then sets bit 13 to 1 if bit 7 of Flagword 5 = 1.

Bit	Meaning
15-14	Not assigned.
13	SPS Engine on (set 1 in P40 to turn on SPS engine, set 0 to turn it off). Also set 0 if caging command received.
12-11	Not assigned.
10	Caution Reset signal (for display system lights). Set to 1 when an error reset key code (from uplink or DSKY) is received.
9	Test connector Outbit. Set 1 in accelerometer reading subroutine ("READACCS", entered about 2 seconds after Average-G is "started" and each two seconds thereafter until bit 1 of Flagword 1 = 0) and set 0 when Average-G is terminated (shortly after bit 6 of Flagword 7 is set 0).
8	Not assigned.
7	Operator error light. Set 0 when an error reset key code (from uplink or DSKY) is received; set 1 if various procedural items (most of which are related to the DSKY, such as illegal noun/verb combinations) are not performed properly.
6	Flash verb and noun lights. Bit is set when an operator action is required (by program means, as a clue to the operator that a response is needed). See discussion of Flagword 4.
5	Key Release light. Set 1 if program desires to use display system but external (DSKY or uplink) use of it is being made. Also would be set 1 if an internal or

Word Number		Contents	
(Cont.)	91-94	Bit	Meaning
		(Cont.) 5	externally initiated monitor display had been started and then some DSKY button was depressed. It is lit if a request for operator response has been initiated and crew does not respond directly to it, but instead displays something else. Set 0 by key release keyboard input, and upon other instances (such as processing of an extended verb) when display system is released by the internal program.
		4	Temperature Caution light. Set bit 15 of IMODES30.
		3	Uplink activity light. Set when an uplink interrupt is received; reset when an error reset key code is received, a key release key code, or at the termination of P27 (based on receipt of a proceed or terminate response).
		2	Computer activity light. Set 0 if no active Jobs are to be performed. During P00 probably will be 0 except during the periodic state vector update or gyro drift compensation. Bit is not set 1 if a Task is performed, but instead left at its previous value.
		1	ISS Warning light. See bits 13, 12, and 10 of IMODES30.

Word 91b, Channel 12. A computer output channel whose individual bits are used for control of optics/TVC and IMU hardware, and for control of the ISS. Set 0 by a fresh start. A restart or V37 processing causes bits 6-4 to be preserved at their present values, and sets remaining bits to 0. Caging command zeros bits 8, 6, 5, 4, and 2.

Bit	Meaning
15	ISS turn-on delay complete. Reset to 0 four seconds after being set 1 at end of 90 second ISS turn-on delay.
14	S4B Cutoff command. Not expected to be generated by programs used during flight.
13	S4B Injection Sequence Start. Not expected to be generated by programs used during flight.
12	Not assigned.

Word Number	Bit	Contents Meaning
(Cont.) 91-94	11	Disengage Optics Digital-to-Analog Converter. Not expected to be generated by programs used during flight (since optics zeroing is initiated only by crew optics switch selection.
	10	Zero Optics. Not expected to be generated by programs used during flight.
	9	S4B Takeover Enable. Set to 1 following a V46E with bits 14-13 of DAPDATR1 = 1 (for Saturn attitude control using RHC). Can be reset to 0 by V37E00E, or a restart (since "Saturn DAP" is not restart protected, cf. bits 15-14 of Flagword 6.
	8	TVC Enable. Set to 1 in P40 shortly after the response to the checklist 0204_8 code, in order to connect the output of the "optics" CDU digital-to-analog converters to the SPS gimbal servo amplifiers. Bit set 0 about 2.5 seconds after engine cutoff command (bit 13 of channel 11 set 0) in the following cases: normal cutoff, a proceed response or a terminate response is provided to the V99N40 flash initiated at nominal ignition -5 seconds, a terminal response is provided to the V97 N40 flash initiated by the thrust fail routine, R40.
	7	Not assigned.
	6	Enable IMU CDU error counters. Set 1 during coarse align of IMU, and in order to permit output of error information to the FDAI attitude error needles (bit is set 0 on initialization pass, then set 1; the third pass is the first one with output to needles).
	5	Zero IMU CDU's. Set to 1 to permit IMU CDU's to be zeroed. This set at the same time as bit 4 of this word when bit 6 of IMODES30 is set 1 (IMU initialization), and is reset 0 about 4 seconds before bit 6 of IMODES30 is set 0. Also set 1 for about 0.32 seconds if a restart encountered with bit 8 of Flagword 0 = 0 (as it is during entry programs).

Word Number	Contents
(Cont) 91-94	Bit — Meaning

4 Enable coarse align of IMU. Set 1 to specify coarse align of IMU (cf. bit 6), and also if middle gimbal angle (i.e. CDUZ exceeds 85^{o}.

3 Not used (assigned to "star trackers on").

2 Enable Optics CDU Error Counters. Set 1 about 0.06 seconds after TVC Enable (bit 8 of this channel) set 1, for TVC control; and set 0 at the same time TVC Enable is zeroed. Set 1 in "T4RUPT" routine (entered every 0.48 seconds) if present value is 0 and computer driving of optics is requested; set 0 if another mode (manual or zero optics) is desired with optics previously having been driven.

1 Zero Optics CDU's. Set 1 for about 0.2 seconds at the end of the optics zeroing sequence (cf. OPTMODES). Not needed for TVC purposes, of course, since these CDU's are optics inputs and TVC merely takes advantage of the digital-to-analog outputs assigned to "optics".

Word 92a, channel 13. A computer output channel whose outputs are used for miscellaneous purposes. Set 0 by a fresh start. A restart or V37 processing (cf. channel 11) causes bits 15-12 and 7-5 to be preserved at their present values, and sets remaining bits to 0.

Bit — Meaning

15 Bit set 1 to permit an internal computer clock (TIME6) to be counted down at a 1600 pps rate. This clock is used for control of jet on-times in RCS DAP and the TVC roll DAP, but is not used for the entry DAP. When clock has counted down, bit is reset to 0, and the desired program interrupt action initiated.

14 Reset input trap circuit 32 , concerned with bits 10-1 of channel 32.

13 Reset input trap circuit 31B, concerned with bits 12-7 of channel 31.

12 Reset input trap circuit 31A, concerned with bits 6-1 of channel 31.

Word Number		Contents
(Cont.) 91-94	Bit	Meaning
	11	Enable Standby. Bit set to 1 at the end of P06 (for an "enter" response to the checklist 00062_8 flash) in order to permit the "PRO" button (formerly "Standby button") to be effective in putting the computer into a period of low power operation. Bit is reset to 0 at the start of P05 if bit 11 of Flagword 5 = 1.
	10	Test DSKY lights. Set 0 by an error reset keycode input; set 1 for about 5 seconds if a verb 35 input is received.
	9	Not assigned.
	8	Not used (assigned to "BMAG output enable").
	7	Telemetry word order code bit. When channel is telemetered, should have a value of 1(bit 0 only for words 1 and 51).
	6	Block inputs to uplink cell. Not set by program.
	5	Not used (connects an alternate input to uplink cell).
	4	Range Unit activity.
	3	Range Unit Select a.
	2	Range Unit Select b.
	1	Range Unit Select c.
	Note:	Bits 1 through 4 are assigned control functions for sampling of the VHF Range link to establish quantity fed to cell 0046_8 (RNRAD). These bits must contain the quantity, 1001_2 in order to obtain this control.

Word 92b, Channel 14. A computer output channel whose outputs are used for control of computer counter cells. Set 0 by a fresh start. A restart or V37 processing (cf.channel 11) causes bit 6 to be preserved at its present value, and sets remaining bits to 0. Caging command zeros bits 15-6.

Bit	Meaning
15	Bit set to 1 to cause output pulses from cell used to drive X-axis IMU CDU error counter (IMU X-axis coarse align or error needle for roll axis). Bit reset to 0 after counter cell reduced to 0 (3200 pps): bit 6 of channel 12 must be set to load error counter.

Word Number	Contents
(Cont.) 91-94	

Bit	Meaning
14	Same as bit 15, but for Y-axis (pitch).
13	Same as bit 15, but for Z-axis (yaw).
12	Bit set to 1 to cause output pulses from cell used to drive optics trunnion or TVC yaw axis. Bit reset to 0 after counter cell reduced to 0 (3200 pps): bit 2 of channel 12 must be set to load error counter.
11	Same as bit 12, but for optics shaft or TVC pitch axis.
10	Bit set 1 to generate gyro torquing pulses, and reset to 0 when required number produced. Is set when pulse torquing of gyros performed (for IMU compensation or for pulse torquing in P52 or P54 following acceptance of V06N93 display).
9	Bit set 1 to indicate negative gyro torquing required (otherwise, torquing is positive). Bit reset to 0 after completion of routine.
8-7	Bits used to specify axis for gyro compensation (sequence is Y, Z, X for inner, middle, outer). Program resets to 00_2 when done.

00_2	No axis
01_2	X-axis
10_2	Y-axis
11_2	Z-axis

6	Bit set 1 (at beginning of routine to generate gyro torquing pulses) to enable gyro torquing power supply, and left at 1 (unless a fresh start done or a caging command).
5	Not used (assigned to entry monitoring function).
4-2	Not assigned.
1	Not used (assigned to "outlink activity").

Word 93a, Channel 30. A computer input channel for miscellaneous functions.

Bit	Meaning
15	Bit sensed as 0 if stable member temperature within design limits (see bit 15 of IMODES30).
14	Bit sensed as 0 if ISS has been turned on or commanded to be turned on (see bit 14 of IMODES30).

Word Number	Contents	
(Cont.) 91-94	Bit	Meaning
	13	Bit sensed as 0 if an IMU fail indication produced (see bit 13 of IMODES30).
	12	Bit sensed as 0 if an IMU CDU fail indication produced (see bit 12 of IMODES30).
	11	Bit sensed as 0 if an IMU cage command generated by the crew (see bit 11 of IMODES30).
	10	Bit sensed as 0 if control of Saturn given to computer.
	9	Bit sensed as 0 if IMU turned on and operating with no malfunctions (see bit 9 of IMODES30).
	8	Not assigned.
	7	Bit sensed as 0 if an optics CDU fail indication produced (see bit 7 of OPTMODES).
	6	Bit sensed as 0 if guidance reference release signal produced: bit not sensed by program.
	5	Bit sensed as 0 if liftoff signal produced (used to cause termination of P02 and initiation of P11, a function that can alternatively be initiated by V75E).
	4	Bit sensed as 0 if S4B separation/abort signal produced: bit not sensed by program.
	3	Bit sensed as 0 when preparations for use of the SPS engine ("SPS ready") is complete. This bit is not sensed by the flight program.
	2	Bit sensed as 0 if CM/SM separation signal produced: bit not sensed by program.
	1	Bit sensed as 0 if "ullage thrust present" (from Saturn): bit not sensed by program.

Word 93b Channel 31. A computer input from crew control devices, used by RCS DAP.

Bit	Meaning
15	Bit sensed as 0 if computer in control of spacecraft ("G&N autopilot control"). Bit also becomes a binary 1 if IMU turned off (hence, due to RCS DAP logic, minimum impulse commands cannot be generated with the IMU turned off).

Word Number	Contents	
(Cont.) 91-94	Bit	Meaning
	14	Bit sensed as 0 if "Free" mode selected.
	13	Bit sensed as 0 if "Hold" mode selected. If bits 14-13 are 11_2, this indicates that "Automatic" mode selected.
	12	Bit sensed as 0 if translation in -Z direction commanded.
	11	Bit sensed as 0 if translation in +Z direction commanded.
	10	Bit sensed as 0 if translation in -Y direction commanded.
	9	Bit sensed as 0 if translation in +Y direction commanded.
	8	Bit sensed as 0 if translation in -X direction commanded.
	7	Bit sensed as 0 if translation in +X direction commanded.
	6	Bit sensed as 0 if rotation in negative roll direction commanded.
	5	Bit sensed as 0 if rotation in positive roll direction commanded.
	4	Bit sensed as 0 if rotation in negative yaw direction commanded.
	3	Bit sensed as 0 if rotation in positive yaw direction commanded.
	2	Bit sensed as 0 if rotation in negative pitch direction commanded.
	1	Bit sensed as 0 if rotation in positive pitch direction commanded.

Word 94a, Channel 32. A computer input channel for additional crew input to RCS DAP, etc.

Bit	Meaning
15	Not assigned.
14	Bit sensed as 0 if "proceed key" (formerly standby button) is depressed (see bit 14 of IMODES33).
13-12	Not assigned.
11	Bit sensed as 0 if spacecraft switch set to indicate that LM attached: bit not used by program (cf. bit 2 of Flagword 7).
10-7	Not assigned.

Word Number	Contents	
(Cont.) 91-94	Bit	Meaning
	6	Bit sensed as 0 if negative roll commanded by minimum impulse controller.
	5	Bit sensed as 0 if positive roll commanded by minimum impulse controller.
	4	Bit sensed as 0 if negative yaw commanded by minimum impulse controller.
	3	Bit sensed as 0 if positive yaw commanded by minimum impulse controller.
	2	Bit sensed as 0 if negative pitch commanded by minimum inpulse controller.
	1	Bit sensed as 0 if positive pitch commanded by minmum impulse controller.

Word 94b, Channel 33. A computer input channel for hardware status and command information. Bits 15-11 are flip-flop bits (which are reset by a channel "write" command) that are also reset when a restart is encountered.

Bit	Meaning
15	Bit sensed as 0 if computer oscillator has stopped (sensed, but with no effect on subsequent program performance, if a restart encountered).
14	Bit sensed as 0 if a computer warning produced (sensed, but with no effect on subsequent program performance, if a restart encountered; formerly, if bits 15-14 = 10_2, it was concluded that a restart loop existed and a fresh start was done: a fresh start can still be forced under this situation by simultaneous depression of optics mark reject and error reset signal (either DSKY).
13	Bit sensed as 0 if an accelerometer fail indication produced (PIPA fail). See bit 13 of IMODES33.
12	Bit sensed as 0 if a telemetry end pulse rejected (downlink interrupt rate excessive). See bit 12 of IMODES33.
11	Bit sensed as 0 if an uplink input bit is rejected, indicating an excessive uplink rate. See bit 11 of IMODES33.

Word Number	Bit	Contents Meaning
(Cont.) 91-94	10	Bit sensed as 0 if spacecraft switches set by crew so as to inhibit uplink inputs from being loaded into erasable memory (an subsequently generating an uplink interrupt). The bit reads a binary 1 when the "accept uplink" signal is present at the interface.
	9-8	Not assigned.
	7	Not used (assigned to "star present").
	6	Not used (assigned to "star tracker on").
	5	Bit sensed as 0 if computer control of optics is set. See bit 5 of OPTMODES.
	4	Bit sensed as 0 if zero optics mode is set. See bit 4 of OPTMODES. If bits 5-4 are both 1, the manual mode is selected.
	3	Not assigned.
	2	Bit sensed as zero if the Range Unit data is good.
	1	Not assigned.
95-97		VGTIGs. The predicted velocity (X, Y, Z) to be gained at TIG in reference coordinates, scaled (meter/centiseconds)/ 2^7. During Lambert burns, the DELVEET3s from pre-thrust targeting are picked up and stored in VGTIG. External ΔV burns compute and store a rotated VG. It is calculated in burn programs: S40.1 computes (X-DELV) or copies (LAMBERT) as part of pre-thrust computations.
98-100		Spares, as defined in words 31-33 of this downlist.

2.2.2.3 Coast and Align List

Contents

Word Number	First Register	Second Register	
1	I.D. (77777_8)	Synch Bits (77340_8)	
2	CSM State Vector (R_X)	CSM State Vector (R_X)	
3	CSM State Vector (R_Y)	CSM State Vector (R_Y)	
4	CSM State Vector (R_Z)	CSM State Vector (R_Z)	
5	CSM State Vector (V_X)	CSM State Vector (V_X)	
6	CSM State Vector (V_Y)	CSM State Vector (V_Y)	
7	CSM State Vector (V_Z)	CSM State Vector (V_Z)	
8	CSM State Vector Time	CSM State Vector Time	
9	Actual X CDU angle	Actual Y CDU angle	
10	Actual Z CDU angle	Optics CDU trunnion angle	
11	ADOTS roll or OGARATE	ADOTS roll or OGARATE	
12	ADOTS pitch or Omega B pitch	ADOTS pitch or Omega B pitch	
13	ADOTS yaw or Omega B yaw	ADOTS yaw or Omega B yaw	
14	X Attitude error	Y attitude error	
15	Z attitude error	RCS flags	
16	THETADX	THETADY	
17	THETADZ	Garbage	
18	TIG	TIG	
19	STARID1	STARID2	
20	MARKTIME1	MARKTIME1	
21	Y CDU angle	Optics shaft angle	} for last MARKTIME1
22	Z CDU angle	Optics trunnion angle	
23	X CDU angle	Garbage	
24	MARKTIME2	MARKTIME2	
25	Y CDU angle	Optics Shaft angle	} for last MARKTIME2
26	Z CDU angle	Optics trunnion angle	
27	X CDU angle	Garbage	
28	Apogee	Apogee	
29	Perigee	Perigee	
30	Delta R	Delta R	
31	VGTIGX	VGTIGX	
32	VGTIGY	VGTIGY	
33	VGTIGZ	VGTIGZ	
34	REFSMMAT (R_1C_1)	REFSMMAT (R_1C_1)	
35	REFSMMAT (R_1C_2)	REFSMMAT (R_1C_2)	
36	REFSMMAT (R_1C_3)	REFSMMAT (R_1C_3)	

Word Number	First Register	Second Register
37	REFSMMAT (R_2C_1)	REFSMMAT (R_2C_1)
38	REFSMMAT (R_2C_2)	REFSMMAT (R_2C_2)
39	REFSMMAT (R_2C_3)	REFSMMAT (R_2C_3)
40	Flagword 0	Flagword 1
41	Flagword 2	Flagword 3
42	Flagword 4	Flagword 5
43	Flagword 6	Flagword 7
44	Flagword 8	Flagword 9
45	DSPTAB+0	DSPTAB+1
46	DSPTAB+2	DSPTAB+3
47	DSPTAB+4	DSPTAB+5
48	DSPTAB+6	DSPTAB+7
49	DSPTAB+8D	DSPTAB+9D
50	DSPTAB+10D	DSPTAB+11D
51	TIME 2	TIME 1
52	LM State Vector (R_X)	LM State Vector (R_X)
53	LM State Vector (R_Y)	LM State Vector (R_Y)
54	LM State Vector (R_Z)	LM State Vector (R_Z)
55	LM State Vector (V_X)	LM State Vector (V_X)
56	LM State Vector (V_Y)	LM State Vector (V_Y)
57	LM State Vector (V_Z)	LM State Vector (V_Z)
58	LM State Vector Time	LM State Vector Time
59	Actual X CDU angle	Actual Y CDU angle
60	Actual Z CDU angle	Optics CDU trunnion angle
61	ADOTS roll or OGARATE	ADOTS roll or OGARATE
62	ADOTS pitch or Omega B pitch	ADOTS pitch or Omega B pitch
63	ADOTS yaw or Omega B yaw	ADOTS yaw or Omega B yaw
64	X attitude error	Y attitude error
65	Z attitude error	RCS flags
66	THETADX	THETADY
67	THETADZ	Garbage
68	* RSBBQ	RSBBQ+1
69	* CADRFLSH	CADRFLSH+1
70	* CADRFLSH+2	FAILREG
71	* FAILREG+1	FAILREG+2
72	Optics shaft	PIPAX
73	PIPAY	PIPAZ

* Indicates two single precision quantities that are not indicated otherwise.

Contents

Word Number	First Register	Second Register
74	OGC	OGC
75	IGC	IGC
76	MGC	MGC
77	Flagword 10	Flagword 11
78	TEVENT	TEVENT
79	LAUNCH AZIMUTH	LAUNCH AZIMUTH
80	OPTMODES	HOLDFLAG
81	LM MASS	CM MASS
82	DAPDATR1	DAPDATR2
83	ERROR X	ERROR Y
84	ERROR Z	Garbage (THETADX)
85	WBODY (roll) or OMEGAC (roll)	WBODY (roll) or OMEGAC (roll)
86	WBODY (pitch) or OMEGAC (pitch)	WBODY (pitch) or OMEGAC (pitch)
87	WBODY (yaw) or OMEGAC (yaw)	WBODY (yaw) or OMEGAC (yaw)
88	REDO COUNTER	Desired FINAL CDU X
89	Desired FINAL CDU Y	Desired FINAL CDU Z
90	IMODES 30	IMODES 33
91	Channel 11	Channel 12
92	Channel 13	Channel 14
93	Channel 30	Channel 31
94	Channel 32	Channel 33
95	DSPTAB+0	DSPTAB+1
96	DSPTAB+2	DSPTAB+3
97	DSPTAB+4	DSPTAB+5
98	DSPTAB+6	DSPTAB+7
99	DSPTAB+8D	DSPTAB+9D
100	DSPTAB+10D	DSPTAB+11D

2.2.2.4 Coast and Align List

Word Number	Contents
1a	I.D. word for this list. It will contain 77777_8.
1b	Synch bits, 77340_8.
2-18	Same as words 2-18 on the Powered List.
19	STAR ID1, 2. The star I.D.'s associated with the sighting vectors in words 21-23 and 25-27. Each star I.D. will be the octal equivalent of the CMC star catalogue number multiplied by six. Each register is scaled (star number × 6)/2^{14}.

Example:

Star	Cat. Number	Downlink Star I.D.
Alpha Tauri	11_8	66_8

BESTI and BESTJ are calculated during PICAPAR and after the astronaut changes the star number.

20	MARKTIME1. The time of the mark (TIME2, TIME1) associated with the data described in words 21-23a, scaled centiseconds/2^{28}.
21-23a	SIGHTING DATA SET1. These five registers contain, in the following order: YCDU angle, optics shaft angle, ZCDU angle, optics trunnion angle and XCDU angle. This data is valid at MARKTIME1 and is associated with the star indexed by BESTI (word 19a). XCDU, YCDU, ZCDU and the optics shaft angle are treated as unsigned 15-bit fractions, scaled degrees/360. The optics trunnion angle is scaled (degrees-19.7754)/45. The bias, 19.7754 is programmed-in.
23b	Garbage. Same as word 30b of the Powered downlist.
24	MARKTIME2. The time of the mark (TIME2, TIME1) associated with the data described in words 25-27a, scaled centiseconds/2^{28}.
25-27a	SIGHTING DATA SET 2. Same as words 21-23a of this list except that this set is associated with MARKTIME2 and Star ID2 indexed by BESTJ (word 19b).
27b	Garbage. The Z component of the third BVECTOR can appear here. In P20 and P23 this register is set to zero. During P22 it is set to the negative value of the first component of the BVECTOR.

Word Number	Contents
28	APOGEE. The altitude of the apogee above a fixed radius, scaled meters/2^{29}. For Earth Orbit it is calculated above the launch pad radius and for Moon Orbit it is computed above the landing-site radius. If Flagword 9, bit 13 (V82EMFLG), is a one, the radius is Moon-centered. A zero in this bit position will indicate an Earth-centered radius. R30 obtains the state vector from precision routines with an indication of the coordinate system. V82EMFLG is then set accordingly. This item is calculated and displayed (V82N44) once if Average G is off and approximately every ten seconds if Average G is on. The maximum value is 9999.9 nmi.
29	PERIGEE. The altitude of the perigee above a fixed radius, scaled meters/2^{29}. For Earth Orbit it is calculated above the launch pad radius and for Moon Orbit it is computed above the landing-site radius. If Flagword 9, bit 13 (V28EMFLG), is a one, the radius is Moon-centered. A zero in this bit position will indicate an Earth-centered radius. R30 obtains the state vector from precision routines with an indication of the coordinate system. V82EMFLG is then set accordingly. This item is calculated and displayed (V82N44) once if Average G is off and approximately every ten seconds if Average G is on. The maximum value is 9999.9 nmi.
30	DELTA R. An approximate measure of the in-plane splash-down error, scaled degrees/360. If the free-fall transfer angle to 300,000 feet above the pad radius is positive, the splash error = free-fall transfer angle + estimated entry angle - range to target. The target location at estimated time of impact is used. If the free-fall transfer angle is negative, the splash error = - range to target. The present target location is used. This parameter is called by V82 if in CSM and if P11 is operating (every 2 seconds).
31-33	Same as words 95-97 of the Powered List.
34-73	Same as words 34-73 of the Powered List.
74-76	OGC, IGC, MGC. During R55, the X, Y, and Z gyro torquing angles. During coarse align, in P52 and P54, the desired gimbal angles (outer, inner & middle), scaled degrees/360.
77	Same as word 77 of the Powered List.
78	Same as word 78 of the Powered List.

Word Number	Contents
79	LAUNCHAZ: The clockwise angle from true north to the IMU stable member X axis, measured in the local horizontal plane and scaled degrees/360. The expected angles will range from $+72^{o}$ to $+108^{o}$ (approx.). The item is pad loaded and may be reloaded during P02, gyrocompassing program, via Verb 78E.
80-94	Same as words 80-94 of the Powered List.
95-100	Same as words 45-50 of the Powered List.

2.2.2.3 Rendezvous and Prethrust List

Contents

Word Number	First Register	Second Register
1	I.D. (77775_8)	Synch Bits (77340_8)
2	CSM State Vector (R_X)	CSM State Vector (R_X)
3	CSM State Vector (R_Y)	CSM State Vector (R_Y)
4	CSM State Vector (R_Z)	CSM State Vector (R_Z)
5	CSM State Vector (V_X)	CSM State Vector (V_X)
6	CSM State Vector (V_Y)	CSM State Vector (V_Y)
7	CSM State Vector (V_Z)	CSM State Vector (V_Z)
8	CSM State Vector Time	CSM State Vector Time
9	Actual X CDU angle	Actual Y CDU angle
10	Actual Z CDU angle	Optics CDU trunnion angle
11	ADOTS roll or OGARATE	ADOTS roll or OGARATE
12	ADOTS pitch or Omega B pitch	ADOTS pitch or Omega B pitch
13	ADOTS yaw or Omega B yaw	ADOTS yaw or Omega B yaw
14	X attitude error	Y attitude error
15	Z attitude error	RCS flags
16	THETADX	THETADY
17	THETADZ	Garbage
18	TIG	TIG
19	T_F Lambert	T_F Lambert
20	RTARGX	RTARGX
21	RTARGY	RTARGY
22	RTARGZ	RTARGZ
23	VHF TIME	VHF TIME
24	MARK TIME	MARK TIME
25	Y CDU angle	Optics shaft angle
26	Z CDU angle	Optics trunnion angle
27	X CDU angle	VHF Range
28	VHF MARKS	OPTIC MARKS
29	TPI TIME	TPI TIME
30	ECSTEER	Garbage
31	DELVTPF (Magnitude)	DELVTPF (Magnitude)
32	Spare	Spare
33	Spare	Spare
34	TPF Time	TPF Time
35	DELVSLV X	DELVSLV X
36	DELVSLV Y	DELVSLV Y
37	DELVSLV Z	DELVSLV Z

Contents

Word Number	First Register	Second Register
38	Range	Range
39	Range Rate	Range Rate
40	Flagword 0	Flagword 1
41	Flagword 2	Flagword 3
42	Flagword 4	Flagword 5
43	Flagword 6	Flagword 7
44	Flagword 8	Flagword 9
45	DSPTAB+0	DSPTAB+1
46	DSPTAB+2	DSPTAB+3
47	DSPTAB+4	DSPTAB+5
48	DSPTAB+6	DSPTAB+7
49	DSPTAB+8D	DSPTAB+9D
50	DSPTAB+10D	DSPTAB+11D
51	TIME 2	TIME 1
52	LM State Vector (R_X)	LM State Vector (R_X)
53	LM State Vector (R_Y)	LM State Vector (R_Y)
54	LM State Vector (R_Z)	LM State Vector (R_Z)
55	LM State Vector (V_X)	LM State Vector (V_X)
56	LM State Vector (V_Y)	LM State Vector (V_Y)
57	LM State Vector (V_Z)	LM State Vector (V_Z)
58	LM State Vector Time	LM State Vector Time
59	Actual X CDU angle	Actual Y CDU angle
60	Actual Z CDU angle	Optics CDU trunnion angle
61	ADOTS roll or OGARATE	ADOTS roll or OGARATE
62	ADOTS pitch or Omega B pitch	ADOTS pitch or Omega B pitch
63	ADOTS yaw or Omega B yaw	ADOTS yaw or Omega B yaw
64	X attitude error	Y attitude error
65	Z attitude error	RCS flags
66	THETADX	THETADY
67	THETADZ	Garbage
68	* RSBBQ	RSBBQ+1
69	* CADRFLSH	CADRFLSH+1
70	* CADRFLSH+2	FAILREG
71	* FAILREG+1	FAILREG+2
72	Optics shaft	PIPAX
73	PIPAY	PIPAZ
74	Elevation angle	Elevation Angle
75	Central Angle	Central Angle

* Indicates two single precision quantities that are not indicated otherwise.

Contents

Word Number	First Register	Second Register
76	Offset Point	Offset Point
77	DELVEET3 X	DELVEET3 X
78	DELVEET3 Y	DELVEET3 Y
79	DELVEET3 Z	DELVEET3 Z
80	OPTMODES	HOLDFLAG
81	LM MASS	CM MASS
82	DAPDATR1	DAPDATR2
83	ERROR X	ERROR Y
84	ERROR Z	Garbage (THETADX)
85	WBODY (roll) or OMEGAC (roll)	WBODY (roll) or OMEGAC (roll)
86	WBODY (pitch) or OMEGAC (pitch)	WBODY (pitch) or OMEGAC (pitch)
87	WBODY (yaw) or OMEGAC (yaw)	WBODY (yaw) or OMEGAC (yaw)
88	REDO COUNTER	Desired FINAL CDU X
89	Desired FINAL CDU Y	Desired FINAL CDU Z
90	IMODES 30	IMODES 33
91	Channel 11	Channel 12
92	Channel 13	Channel 14
93	Channel 30	Channel 31
94	Channel 32	Channel 33
95	RTHETA	RTHETA
96	GEODETIC LAT	GEODETIC LAT
97	LONG	LONG
98	V PRED	V PRED
99	GAMMA(EI)	GAMMA(EI)
100	Flagword 10	Flagword 11

Word Number	Contents
1a	I.D. word for this list. It will contain 77775_8.
1b	Synch bits, 77340_8.
2-22	Same as words 2-22 on Powered List.
23	VHF TIME. The time (TIME2, TIME1) of the last VHF Range mark, scaled centiseconds/2^{28}. This item is calculated each time the VHF Range is read. It is also used to determine if one minute has elapsed since the last mark was processed and to integrate the state vector to the mark-time.
24	OPTICS MARKTIME. The time of mark (TIME2, TIME1) associated with the data described in words 25-27a, scaled centiseconds/2^{28}.
25-27a	SIGHTING DATA. These five registers contain, in the following order: YCDU angle, optics shaft angle, ZCDU angle, optics trunnion angle and XCDU angle. This data is valid at the time an optics mark is taken on the LM vehicle during rendezvous tracking (P20). XCDU, YCDU, ZCDU and optics shaft angle are unsigned 15-bit fractions, scaled degrees/360. The trunnion angle is a 14-bit signed fraction scaled, (degrees -19.7754)/45 (two's complement). The bias, 19.7754, is programmed-in.
27b	VHF RANGE. (Raw Data). The range from the CSM to the LM as measured by the VHF range link, using the Rendezvous Tracking Data Processing Routine. This quantity is a 15-bit integer with the least significant bit equal to 0.01 nmi. (multiply by 18.52 to obtain meters). Whenever the VHF Range Flag is found to be set, the routine (R22) reads the range value if at least 60 seconds have expired since the time of last reading. If so, the t_{VHF} is updated to the present time and a VHF range reading made. It is assumed, for practical purposes, that the range data is acquired at this present t_{VHF} but there actually is a very small time delay.
28a	VHF MARKS. The number of VHF ranging marks incorporated into the state vector since the initialization of P20, scaled 2^{-14}. This value is used in the N45 display and has a range of 0 to 99. VHFCNT is incremented each time a VHF ranging mark is incorporated (approx. 1/min if P20 is operating, VHF ranging is on and VHFRFLAG, UPDATFLAG and TRACKFLAG are set).

[X] Revised
[ ] Added
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Word Number	Contents
28b	OPTIC MARKS. The number of optic marks incorporated into the state vector since the initialization of P20, scaled 2^{-14}. This item is used in the N45 display and has a range of 0 to 99. TRKMKCNT is incremented each time an optics mark is incorporated. The frequency depends upon the astronaut because marking is a manual operation.
29	TPI TIME. The time of ignition for the Rendezvous programs, scaled centiseconds/2^{28}. An estimate of this item can be calculated in P17 and then modified in P34 or left the same in P38. It can also be inputted via the DSKY.
30a	ECSTEER. A pad-load erasable which may be used by P40 to set CSTEER, the constant "c" in the cross-product steering equation: $\Delta m = c\underline{b}\Delta t - \Delta\underline{v}$, and in certain prethrust computations for P40/41. It is scaled as a 14-bit fraction/4. P34, P35, P38, P39 and P17 will set ECSTEER = 1.0. P37 will set ECSTEER = 0.5 whereas in P31 the value of "c" is determined by RTCC and uplinked with other target parameters. Values for "C" from -4.0 to +4.0 (less 1 bit) can be handled. The MIT standard is 1.0, except for P37 where 0.5 is used. Once set up prior to a burn, ECSTEER should be constant throughout the burn and post-burn sequences.
30b	Garbage. This register may contain any of the following: (a) DVTOTAL, the summation of the magnitude of the Delta V's and also R3 of the N40 display during the P40, powered flight maneuver. This item is zeroed by PREREAD (TIG-30) and also shortly after entering P40. It is updated every 2 sec by SERVICER (after PIPA compensation). (b) END-DELV, the External Delta V Update. (c) DEL, MFI, MFS, three names given to the first of eighteen storage locations used for storing matrix information in the KALCMANU computations.
31	DELVTPF. The difference between the absolute velocities of the passive and active vehicles at intercept time [ABVAL (VPASS4 - VTPRIME)], scaled (meters/centisecond)/2^{7}. This quantity is calculated once for each pass through either P34 or P38.
32-33	Spares. The description will be the same as the one used for word 31 in the Powered List.

Word Number	Contents
34	TPF TIME. The time of intercept for the various rendezvous programs, scaled centisecond/2^{28}. It is one of the variables used in the determination of the required delta velocity for a rendezvous maneuver. It is calculated in P34/P74, P38/P78 and inputted to the midcourse programs, P35/P75 and P39/P79.
35-37	P30 DELV's. An impulsive Delta V in the local vertical coordinates of the active vehicle at the time of ignition specified by the astronaut (V06N81) or uplink and scaled, meters/centiseconds/2^{7}. The local vertical coordinate system may be either earth-centered or moon-centered. There is no flagbit to indicate the origin point. The P30 ΔV vector is rotated into a basic reference coordinate system for use by P40 or P41.
38	RANGE. This parameter is involved in two areas, R31/R34 and R36. In either category it is scaled, meters/2^{29}. In R31/R34, RANGE is the magnitude of the difference between the two vehicles' (CSM-LM), radius vectors. In R36, RANGE represents the out-of-plane position and is computed as $Y = \underline{r}_C \cdot \left\{\text{Unit } (\underline{V}_L \times \underline{r}_L)\right\}$. This item is calculated whenever R31, R34 or R36 is selected by the astronaut via V83, V85, or V90. The displayed value can range from 000.00 nmi. to 999.99 nmi. Once the routine is selected, RANGE is recomputed every 0.5 sec in R31/R34 until program termination ("PROCEED"); in R36 it is necessary to "RECYCLE" in order to have the value recomputed.
39	RRATE. This parameter is involved in two area, R31/R34 and R36. It is scaled (meters/centisecond)/2^{7}. In R31/R34 it is defined as the range rate between the two vehicles (CSM-LM) and is computed as $\dot{R} = (\underline{V}_L - \underline{V}_C) \cdot \left\{\text{UNIT } (\underline{R}_L - \underline{R}_C)\right\}$. A negative quantity indicates closing. In R36, RRATE represents velocity in the sense of $\dot{Y} = \underline{V}_C \cdot \left\{\text{UNIT } (\underline{V}_L \times \underline{r}_L)\right\}$. This item is calculated whenever R31, R34, or R36 is selected by the astronaut using verbs V83, V85, or V90. The displayed value can range from 0000.0 ft/s to 9999.9 ft/s. It is recomputed every 0.5 second in R31/R34 until program termination ("PROCEED"). In R36 it is necessary to RECYCLE in order to update the value, which is valid for an astronaut-selected time.
40-76	Same as words 40-76 of the Powered List.

Word Number	Contents
77-79	P31 DELVEET3s. The impulsive DELTA V (X, Y, Z) calculated via the Lambert routine, scaled (meters/centisecond)/2^7. These quantities are based on the uplinked offset - target vector, time of ignition, and transfer time. They are calculated once and are used only for display purposes during P31. The Reference Coordinates may be either moon- or earth-centered. The system in use is indicated by the contents of erasable register, RTX2. If RTX2=0 the system is earth-centered but, if RTX2=2, the system is moon-centered.
80-94	Same as words 80-94 of the Powered List.
95	RTHETA serves two areas, R31/R34 and R36. In R31/R34 it is the angle from the local horizontal plane to either the CSM X-body axis (Noun 54 flashing) or to the SXT line of sight (Noun 53 flashing). In R36 it is the angle between the line of sight and the forward direction, measured in the local horizontal plane. The scaling, in both conditions, is in degrees/360. This item is calculated whenever R31, R34 or R36 is selected by the astronaut via V83, V85, or V90. It is computed every 0.5 second in R31/R34 until program termination ("PROCEED"). In P36, it is necessary to "RECYCLE" in order to have the value recomputed.
96	LAT(SPL). The latitude of the landing site (earth), scaled degrees/360. It is used only for DSKY display and is calculated and displayed at the end of both the conic phase and also the precision phase of the Return to Earth program. The range of values is from -90° to $+90^{\circ}$. A negative value indicates south of the equator, whereas a positive one denotes north of the equator.
97	LNG(SPL). The longitude of the landing site (earth), scaled degrees/360. The range of values is from -180° to $+180^{\circ}$. A negative quantity indicates west of Greenwich, whereas a positive one denotes east of Greenwich. This item is used for DSKY display only and is calculated and displayed at the end of both the conic phase and the precision phase of the Return to Earth program.

Word Number	Contents
98	VPRED. The predicted velocity magnitude at an entry altitude of 400,000 ft above the Fischer Ellipsoid, scaled (meters/centisecond)/2^7. The range of values is from +75 meters/centisecond to +115 meters/centisecond. This item is used for DSKY display only and is calculated and displayed at the end of both the conic phase and the precision phase of the Return to Earth program.
99	GAMMAEI. The flight path angle between the inertial velocity vector and the local horizontal at the entry interface altitude of 400,000 ft. above the Fischer Ellipsoid, scaled degrees/360. The range of values runs from -1° to -7° and is used for display only. A negative value indicates that the flight path is below the horizontal plane. This item is calculated and displayed at the end of both the conic and precision phases of the Return to Earth program.
100	Same as word 77 of the Powered List.

2.2.2.7 Entry and Update List

Contents

Word Number	First Register	Second Register
1	I.D. (77776_8)	Synch Bits (77340_8)
2	CSM State Vector (R_X)	CSM State Vector (R_X)
3	CSM State Vector (R_Y)	CSM State Vector (R_Y)
4	CSM State Vector (R_Z)	CSM State Vector (R_Z)
5	CSM State Vector (V_X)	CSM State Vector (V_X)
6	CSM State Vector (V_Y)	CSM State Vector (V_Y)
7	CSM State Vector (V_Z)	CSM State Vector (V_Z)
8	CSM State Vector Time	CSM State Vector Time
9	Actual X CDU angle	Actual Y CDU angle
10	Actual Z CDU angle	Optics CDU trunnion angle
11	ADOTS roll or OGARATE	ADOTS roll or OGARATE
12	ADOTS pitch or Omega B pitch	ADOTS pitch or Omega B pitch
13	ADOTS yaw or Omega B yaw	ADOTS yaw or Omega B yaw
14	X attitude error	Y attitude error
15	Z attitude error	RCS flags
16	THETADX	THETADY
17	THETADZ	Garbage
18	ENTRY DAP MODE	PREL (roll rate)
19	QREL (pitch rate)	RREL (yaw rate)
20	L/D1	L/D1
21	* UPBUFF	UPBUFF+1
22	* UPBUFF+2	UPBUFF+3
23	* UPBUFF+4	UPBUFF+5
24	* UPBUFF+6	UPBUFF+7
25	* UPBUFF+8D	UPBUFF+9D
26	* UPBUFF+10D	UPBUFF+11D
27	* UPBUFF+12D	UPBUFF+13D
28	* UPBUFF+14D	UPBUFF+15D
29	* UPBUFF+16D	UPBUFF+17D
30	* UPBUFF+18D	UPBUFF+19D
31	COMPNUMB	UPOLDMOD
32	UPVERB	UPCOUNT
33	Roll error	Roll angle
34	LATANG	LATANG
35	RDOT	RDOT
36	THETAH	THETAH
37	GEODETIC LAT (SPLSH)	GEODETIC LAT (SPLSH)
38	LONG (SPLSH)	LONG (SPLSH)

* Indicates two single precision quantities that are not indicated otherwise.

Contents

Word Number	First Register	Second Register
39	ALPHA	BETA
40	Flagword 0	Flagword 1
41	Flagword 2	Flagword 3
42	Flagword 4	Flagword 5
43	Flagword 6	Flagword 7
44	Flagword 8	Flagword 9
45	DSPTAB+0	DSPTAB+1
46	DSPTAB+2	DSPTAB+3
47	DSPTAB+4	DSPTAB+5
48	DSPTAB+6	DSPTAB+7
49	DSPTAB+8D	DSPTAB+9D
50	DSPTAB+10D	DSPTAB+11D
51	TIME 2	TIME 1
52	PIPTIME1	PIPTIME1
53	DELVX	DELVX
54	DELVY	DELVY
55	DELVZ	DELVZ
56	TTE (EMS)	TTE (EMS)
57	VIO	VIO
58	VPRED (EI)	VPRED (EI)
59	Actual X CDU angle	Actual Y CDU angle
60	Actual Z CDU angle	Optics CDU trunnion angle
61	ADOTS roll or OGARATE	ADOTS roll or OGARATE
62	ADOTS pitch or OMEGA B pitch	ADOTS pitch or OMEGA B pitch
63	ADOTS yaw or OMEGA B yaw	ADOTS yaw or OMEGA B yaw
64	X attitude error	Y attitude error
65	Z attitude error	RCS flags
66	ERROR X	ERROR Y
67	ERROR Z	THETADX
68	THETADY	THETADZ
69	ENTRY DAP MODE	PREL (roll rate)
70	QREL (pitch rate)	RREL (yaw rate)
71	UPBUFF	UPBUFF+1
72	UPBUFF+2	UPBUFF+3
73	UPBUFF+4	UPBUFF+5
74	UPBUFF+6	UPBUFF+7
75	UPBUFF+8D	UPBUFF+9D

Contents

Word Number		First Register	Second Register
76		UPBUFF+10D	UPBUFF+11D
77		UPBUFF+12D	UPBUFF+13D
78		UPBUFF+14D	UPBUFF+15D
79		UPBUFF+16D	UPBUFF+17D
80		UPBUFF+18D	UPBUFF+19D
81		LM MASS	CM MASS
82		DAPDATR1	DAPDATR2
83		Roll Angle	Roll Command
84		OPTMODES	HOLDFLAG
85		WBODY (roll) or OMEGAC (roll)	WBODY (roll) or OMEGAC (roll)
86		WBODY (pitch) or OMEGAC (pitch)	WBODY (pitch) or OMEGAC (pitch)
87		WBODY (yaw) or OMEGAC (yaw)	WBODY (yaw) or OMEGAC (yaw)
88		REDO COUNTER	Desired Final CDU X
89		Desired FINAL CDU Y	Desired FINAL CDU Z
90		IMODES 30	IMODES 33
91		Channel 11	Channel 12
92		Channel 13	Channel 14
93		Channel 30	Channel 31
94		Channel 32	Channel 33
95	*	RSBBQ	RSBBQ+1
96	*	CADRFLSH	CADRFLSH+1
97	*	CADRFLSH+2	FAILREG
98	*	FAILREG+1	FAILREG+2
99		Flagword 10	Flagword 11
100		GAMMA (EI)	Range for Initialization

* Indicates two single precision quantities that are not indicated otherwise.

2.2.2.8 Entry and Update List

Word Number	Contents
1a	I.D. word for this list. It will contain 77776_8.
1b	Synch bits. It will contain 77340_8.
2-17	Same as words 2-17 on the Powered List.
18a	ENTRY DAP MODE. A 4-position switch specifying branching in ENTRY DAP, scaled 2^{-14}. Set to "-1" (77776_8) if entry equations sense drag in excess of 0.05 g. Set to "-0" (77777_8) if the ALFA angle (pitch attitude) magnitude is greater than 135°. Set to "+1" (00001_8) if the ALFA angle magnitude is in the range 45°-135°. Set to "+0" (00000_8) if the ALFA angle is less than 45°. The expected value sequence would be, +1→+0→-1. The value, -0, is not generally expected. This item is calculated each 0.1 second after the DAP is turned on in P62. Flagword 6, bits 12 and 2, indicates an active DAP.
18b, 19	PREL, QREL, RREL. The single-precision roll, pitch and yaw rates, components of the CM angular velocity vector along the body X, Y, and Z axes and scaled (degrees/sec)/1800. All are corrected for $\dot{\gamma}_E$ if $\dot{\gamma}_E > \dot{\gamma}_E$ min. The expected range of values would be: PREL ± 20°/sec, QREL ± 4°/sec, RREL≈± 17°/sec. These quantities are calculated each 0.1 sec after the DAP is turned on in P62. The functioning is indicated by non-zero values in both bit 1 and bit 2 of flagword 6.
20	L/D1. The commanded value of lift-to-drag ratio used in Reentry Steering to provide Roll Command, scaled 2^0. It is computed whenever lateral logic is exercised, normally each 2 seconds after the initiation of P64 until the velocity becomes less than 1000 ft/sec in P67. The value range should be equal to, or less than, 1.0. It is omitted in P66. LAD is pad loaded.

Word Number	Contents
21-30	UPBUFF's. These twenty registers, UPBUFF through UPBUFF +19D, contain the uplinked octal components in the transmitted order. If the update is composed of less than twenty quantities, the remaining registers will contain garbage.
31a	COMPNUMB. The total number (octal) of components the update program expects to receive. For a Verb 71 or a Verb 72 update, COMPNUMB will be set equal to the index value.
31b	UPOLDMOD. This is the number of the CMC program which was interrupted by P27, the update program. It will indicate program 0, 2, or Fresh Start (-0_8).
32a	UPVERB. The least significant digit of the verb number which was selected to initiate a desired CMC update.
32b	UPCOUNT. The octal identifier of the next quantity that the update program expects to receive. As each quantity goes into UPBUFF, UPCOUNT will be incremented by one, until it is equal to COMPNUMB. It will not change during a line-by-line correction of the data load.
33a	ROLL ERROR. The CM roll attitude error in body axes generated by the DAP and displayed on the FDAI needle, scaled degrees/360. The error is integrated each 0.1 sec between 2-second DAP updates. This quantity is the same as the item, AK, except for the scale factor, and is active only after the DAP is turned on in P62. A one in bit 12 of flagword 6 indicates such activity.
33b	ROLL ANGLE. The roll attitude angle used by ENTRY DAP, scaled degrees/180. It is the first Euler rotation of the CM body triad about the negative relative velocity vector -UVA, along which UBX points. The value ranges ± 360°, is calculated after the DAP is turned on in P62 and is updated each 0.1 second during its operating period. Operation is indicated by a non-zero in bit 12 of flagword 6.
34	LATANG. The lateral range expressed as an angle, scaled radians/4. It will range at less than 200 nmi and is calculated each 2 seconds after the initiation of P63 until the end of P67.

Word Number	Contents
35	RDOT. Altitude rate. The radial component of velocity (negative if descending), scaled (feet/sec)/(2 × 25766.1973). This is a scalar component calculated in earth-centered reference coordinates. If bit 9, flagword 6 (RELVELSW) is zero, the velocity used is inertial. If bit 9, flagword 6 is a one, a velocity relative to air mass is used. The expected range of values runs from less than -7000 ft/sec to +1000 ft/sec and is calculated each 2 seconds after P63 until the end of P67.
36	THETAH. The range between the present position and the estimated landing site, expressed as an angle and scaled, degrees/360. The expected value is less than 180°. It is calculated each 2 seconds after P63 until the end of P67. It is used in P61 for computing EMS display but is not on the Powered Flight downlist, however.
37	LAT(SPL). The geodetic latitude of the entry target, scaled degrees/360. A positive quantity denotes North while a negative quantity indicates South. This parameter is pad loaded or DSKY loaded when P61 or P62 is in progress. It is also computed in P37 (Return to Earth) and displayed.
38	LONG(SPL). The longitude of the entry target scaled, degrees/360. A positive quantity indicates East while a negative quantity denotes West. This parameter is pad loaded or DSKY loaded when P61 or P62 is in progress. It is also computed in P37 (Return to Earth) and displayed.
39a	ALPHA. The pitch attitude angle, used by ENTRY DAP and scaled, degrees/180. It is the third rotation of the CM body triad in the Euler sequence R, β, α, and is about UBY. The value range is $\pm 180^{\circ}$ and is calculated each 0.1 second after the DAP is turned on in P62. Operation of such is indicated by a non-zero value in bit 12, flagword 6. (Bits 1 and 2 are also non-zero.)
39b	BETA. The yaw attitude angle, used by ENTRY DAP and scaled degrees/180. It is the second rotation of the CM body triad in the Euler sequence R, β, α, and is about UBZ. The range is $\pm 90^{\circ}$ and is calculated each 0.1 second after the DAP is turned on in P62. This state is indicated by a non-zero value in bit 12, flagword 6. (Bits 1 and 2, flagword 6, will also be zero.)

Word Number	Contents
40-51	Same as words 40-51 of the Powered List.
52	Same as word 24 of the Powered List.
53-55	Same as words 25-27 of the Powered List.
56	TTE(EMS). The time required to traverse the conic path from the present position to the specified EMS altitude above the Fischer ellipsoid, expressed as a negative number, counting down and scaled, centisecond/2^{28}. The value is $<$ 40 min and is calculated in a one-shot fashion in P 61. TTE is stored when generated in P61. It will be decremented once just prior to display via N63 to account for time lapse. Thus, this parameter will change twice during P61; once when calculated and once when displayed. This change will not be seen if the Powered Flight downlist is used during P61 but will appear if the Entry and Update List becomes the P61 List.
57	VIO. The predicted entry velocity at the EMS altitude above the Fischer radius along a conic path from the present position, scaled (meters/centisecond)/2^{7}. The value will be approximately 38,000ft/s and be calculated once in P61.
58	VPRED(EI). The predicted entry velocity at 400K feet above the Fischer radius along a conic path from the present position, scaled (meters/centisecond)/2^{7}. The value will be approximately 38K ft/s and be calculated once, in P61.
59-65	Same as words 59-65 on the Powered List.
66-67a	Same as words 83, 84a on the Powered List.
67b-68	Same as words 16, 17a on the Powered List.
69-70	Repeat of words 18-19 of this list.
71-80	Repeat of words 21-30 of this list.
81-82	Same as words 81-82 on the Powered List.
83a	Same as word 33b of this list.
83b	ROLL COMMAND. The most significant half of roll attitude command issued by Entry Guidance equations and used by the Entry DAP, scaled degrees/360. The angle is defined as a rotation about the negative relative velocity vector, $-\underline{V}_{REL}$. The value will range ± 180° and is initially set in P62, based on HEADSUP, and holds until the drag exceeds 0.05 g. The quantity will be changed each 2 seconds after P64 until P67.

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[ ] Added GSOP # R-577 PCR # 237 Rev. 2 Date 8/1/68

Word Number	Contents
84	Same as word 80 on the Powered List.
85-94	Same as words 85-94 on the Powered List.
95-98	Same as words 68-71 on the Powered List.
99	Same as word 77 on the Powered List.
100a	GAMMA(EI). The conic flight path angle between the inertial velocity and the local horizontal at the entry interface altitude of 400,000 ft above the Fischer ellipsoid, scaled degrees/360. A minus quantity indicates that the flight path is below the horizontal plane. This item is calculated once, in P61.
100b	RANGE for INITIALIZATION. The predicted range angle from the EMS altitude above Fischer radius to target along conic from present position, scaled degrees/360. This value is calculated once, in P61.

REENTRY and DAP SHARING of DOWNLIST REGISTERS

Words 11-13 ADOT, ...+5 = XPIPBUF, YPIPBUF, ZPIPBUF — PIPA Buffers for TM during ENTRY. PIPs filed here every 0.5 second.
XOLDBUF, YOLDBUF, ZOLDBUF — Contain PIPA value previously in PIPBUF.
Scaled (centimeters/second)/(5.85×2^{14}).

Word 16a THETADX = QAXERR, Pitch attitude error. Scaled degrees/180.

Word 16b THETADY = RAXERR, Yaw attitude error. Scaled degrees/180.

Word 17a THETADZ = Q7, (high order register) minimum drag for UPCONTROL (The low-order register information is lost). Scaled $(ft/sec^2)/805$.

Word 21a UPBUFF = CMTMTIME, Time at which body-rate list was last initialized. Scaled centiseconds/2^{28}.

Word 21b UPBUFF +1 = SW/NDX, Combined switch and index associated with FDAI display and TM. See COLOSSUS GSOP Section 3 page 3.4-72.

Words 22a-29a UPBUFF +2,
... +16D = Body rates in the sequence, PREL, QREL, RREL, PREL, QREL, RREL, etc. Scaled (degrees/sec)/1800.

Words 29b, 30a UPBUFF +17D,
...+18D = V1, initial velocity for UPCONTROL. Scaled (ft/sec)/2 × 25766.1973.

Word 30b UPBUFF +19D = A0 (high order register) initial drag for UPCONTROL. Scaled (ft/sec)/805.0.

Word 56 TTE, ...+1 = L/DCALC, onboard estimate of L/D ratio. Scaled 2^{0} (max. value of 1.0).

Word 57 VIO, ...+1 = LEWD, UPCONTROL reference, L/D. Scaled 2^{0} (max. value of 1.0).

Word 58 VPRED, ...+1 = VL, exit velocity for UPCONTROL. Scaled (ft/sec)/ 2 × 25766.1973.

Word 66a ERRORX = VDT/180, preselected drifting rate used by Roll DAP (0 = DAP in dead zone). Scaled (deg/sec)/90.

Word 66b ERRORY = VT/180E, minus roll rate used by the Roll DAP update cycle. Scaled (-deg/sec)/90.

Words 85-87 WBODY, ...+5
= ASKEP, Keppler range.
ASP1, final phase range.
ASPUP, Up-range.
ASPDN, range down to PULL-UP.
ASP3 (double-precision) gamma correction.
All scaled, deg/360.

Words 88b, 89 THETAD, ...+2
= RDOTREF (double-precision), reference RDOT for UPCONTROL. VREF (high-order register only), reference velocity for UPCONTROL. Both scaled (ft/sec)/2 × 25766.1973.

Word 100 GAMMAEI, ...+1

First Time Sharing = GAMMAL (double-precision), flight-path angle at VL. Scaled deg/(180/π).

Second Time Sharing = PREDANG (single-precision), predicted range, final phase.
JJ (single-precision), index in final phase, table look-up. Both scaled, nm/2700.

2.2.2.9 Program 22 List

Contents

Word Number	First Register	Second Register
1	I.D. (77773_8)	Synch bits (77340_8)
2	CSM State Vector (R_X)	CSM State Vector (R_X)
3	CSM State Vector (R_Y)	CSM State Vector (R_Y)
4	CSM State Vector (R_Z)	CSM State Vector (R_Z)
5	CSM State Vector (V_X)	CSM State Vector (V_X)
6	CSM State Vector (V_Y)	CSM State Vector (V_Y)
7	CSM State Vector (V_Z)	CSM State Vector (V_Z)
8	CSM State Vector Time	CSM State Vector Time
9	Actual X CDU angle	Actual Y CDU angle
10	Actual Z CDU angle	Optics CDU trunnion angle
11	ADOTS roll or OGARATE	ADOTS roll or OGARATE
12	ADOTS pitch or Omega B pitch	ADOTS pitch or Omega B pitch
13	ADOTS yaw or Omega B yaw	ADOTS yaw or Omega B yaw
14	X attitude error	Y attitude error
15	Z attitude error	RCS flags
16	THETADX	THETADY
17	THETADZ	Garbage
18	MARKTIME for first mark	MARKTIME for first mark
19	INNER GIMBAL ANGLE	SHAFT ANGLE
20	MIDDLE GIMBAL ANGLE	TRUNNION ANGLE
21	OUTER GIMBAL ANGLE	Most significant part of MARKTIME for second mark
22	Least significant part of MARK-TIME for second mark	INNER GIMBAL ANGLE
23	SHAFT ANGLE	MIDDLE GIMBAL ANGLE
24	TRUNNION ANGLE	OUTER GIMBAL ANGLE
25	MARKTIME for third mark	MARKTIME for third mark
26	INNER GIMBAL ANGLE	SHAFT ANGLE
27	MIDDLE GIMBAL ANGLE	TRUNNION ANGLE
28	OUTER GIMBAL ANGLE	Most significant part of MARKTIME for fourth mark
29	Least significant part of MARK-TIME for fourth mark	INNER GIMBAL ANGLE
30	SHAFT ANGLE	MIDDLE GIMBAL ANGLE
31	TRUNNION ANGLE	OUTER GIMBAL ANGLE
32	MARKTIME for fifth mark	MARKTIME for fifth mark
33	INNER GIMBAL ANGLE	SHAFT ANGLE
34	MIDDLE GIMBAL ANGLE	TRUNNION ANGLE

Contents

Word Number		First Register	Second Register
35		OUTER GIMBAL ANGLE	Garbage
36		LANDMARK	Garbage
37		Spare	Spare
38		Spare	Spare
39		Spare	Spare
40		Flagword 0	Flagword 1
41		Flagword 2	Flagword 3
42		Flagword 4	Flagword 5
43		Flagword 6	Flagword 7
44		Flagword 8	Flagword 9
45		DSPTAB+0	DSPTAB+1
46		DSPTAB+2	DSPTAB+3
47		DSPTAB+4	DSPTAB+5
48		DSPTAB+6	DSPTAB+7
49		DSPTAB+8D	DSPTAB+9D
50		DSPTAB+10D	DSPTAB+11D
51		TIME 2	TIME 1
52		LANDMARK LATITUDE	LANDMARK LATITUDE
53		LANDMARK LONGITUDE	LANDMARK LONGITUDE
54		LANDMARK ALTITUDE	LANDMARK ALTITUDE
55		Spare	Spare
56		Spare	Spare
57		Spare	Spare
58		Spare	Spare
59		Actual X CDU angle	Actual Y CDU angle
60		Actual Z CDU angle	Optics CDU trunnion angle
61		ADOTS roll or OGARATE	ADOTS roll or OGARATE
62		ADOTS pitch or Omega B pitch	ADOTS pitch or Omega B pitch
63		ADOTS yaw or Omega B yaw	ADOTS yaw or Omega B yaw
64		X attitude error	Y attitude error
65		Z attitude error	RCS flags
66		THETADX	THETADY
67		THETADZ	Garbage
68	*	RSBBQ	RSBBQ+1
69	*	CADRFLSH	CADRFLSH+1
70	*	CADRFLSH+2	FAILREG
71	*	FAILREG+1	FAILREG+2
72		Optics Shaft	PIPAX

* Indicates two single precision quantities that are not indicated otherwise.

Word Number	First Register	Second Register
73	PIPAY	PIPAZ
74	Number of Marks	Garbage
75	Flagword 10	Flagword 11
76	Landing Site Vector X comp.	Landing Site Vector X comp.
77	Landing Site Vector Y comp.	Landing Site Vector Y comp.
78	Landing Site Vector Z comp.	Landing Site Vector Z comp.
79	Spare	Spare
80	OPTMODES	HOLDFLAG
81	LM MASS	CM MASS
82	DAPDATR1	DAPDATR2
83	ERROR X	ERROR Y
84	ERROR Z	Garbage (THETADX)
85	WBODY (roll) or OMEGAC (roll)	WBODY (roll) or OMEGAC (roll)
86	WBODY (pitch) or OMEGAC (pitch)	WBODY (pitch) or OMEGAC (pitch)
87	WBODY (yaw) or OMEGAC (yaw)	WBODY (yaw) or OMEGAC (yaw)
88	REDO COUNTER	Desired FINAL CDU X
89	Desired FINAL CDU Y	Desired FINAL CDU Z
90	IMODES 30	IMODES 33
91	Channel 11	Channel 12
92	Channel 13	Channel 14
93	Channel 30	Channel 31
94	Channel 32	Channel 33
95	Spare	Spare
96	Spare	Spare
97	Spare	Spare
98	Spare	Spare
99	Spare	Spare
100	Spare	Spare

2.2.2.10 Program 22 List

Word Number	Contents
1a	I.D. word for this list, 77773_8.
1b	Synch bits, 77340_8.
2-17	Same as words 2-17 on the Powered List.
18-35a	LANDING SITE MARK DATA. These thirty-five registers contain the mark data which is being used to update the CSM state vector and the landmark position coordinates. Each mark, of which five are allowed, consists of six parameters stored in seven registers. These quantities, listed in the correct transmitted order, are:

Time since epoch (double precision) scaled centiseconds/2^{-28}.

Inner gimbal angle (CDUY)
Optics Shaft angle
Middle gimgal angle (CDUZ)

15-bit unsigned fractions, scaled degrees/360.

Optics Trunnion angle, scaled (degrees-19.7754)/45 (two's complement). The bias, 19.7754, is programmed-in.

Outer gimbal angle (CDUX). A 15-bit unsigned fraction, scaled degrees/360.

SVMRKDAT through SVMRKDAT +34 is set at the beginning of P22 after the operation of the Sighting Mark Routine, R53. R53 leaves the mark data in the VAC area and, for simplicity, P22 moves a total of 36 registers via a six-cycle loop of a VLOAD followed by a STORE instruction. P22 performs in this manner not caring whether the number of marks is one or five. P22 clears flag, P22MKFLG, before moving the mark data and sets it after moving the data to signify that the SVMRKDAT table contains the latest mark data. If CMOONFLG, bit 12, Flagword 8, is a zero, the coordinate system is earth-centered. A one in this bit position would indicate a moon-centered coordinate system.

Word Number	Contents
35b	Garbage. This register will contain an indeterminable background quantity from the 36th register of the Marking program, SXTMARK.
36a	LANDMARK ID contains the R2 entry by the astronaut after a V05N70 or V05N71 action. It contains five octal digits, ABCDE, which describe the landmark as follows: A = 1 if landmark is known. A = 2 if landmark is unknown. B = index of offset designator. C = not used. DE = 00 for a landmark whose coordinates are not stored in the CMC memory. = 01 for the landing site. = 02 through 32_8 for the index number whose coordinates are stored in the CMC fixed memory. The offset indicator, B, is set to zero at the start of P22. The astronaut may change all items after a V05N70 or V05N71. It is used by P22 after each of these verbs to extract the information described above.
36b	Garbage. This register is used for the low-order register of the first component of the VMOON vector and also by the item, HORIZON (the P23 horizon identification).
37-39	SPARES. Same description as word 31 of the Powered List.
40-51	Same as words 40-51 on the Powered List.
52	LANDMARK LATITUDE is the latitude of the landmark which P22 is updating, scaled degrees/360. It may be either earth-centered or moon-centered. If, upon entry of P22, CMOONFLG (Flagword 8, bit 12) equals zero, the coordinate system is earth-centered. Conversely, the coordinate system will be moon-centered if CMOONFLG equals one. It does not change within P22. The landmark may be either known or unknown. If known, it may be either entered by the astronaut, obtained from landmark tables stored in the fixed memory, or obtained from the item, RLS (lunar landing site). The range of values is $-.25$ revolutions $\leq$ LAT $\leq .25$ revolutions. The latitude is computed for known landmarks only at the start of P22. At the completion of P22, the latitude is computed for all landmarks and contains the updated value. Item LANDLAT occupies the same locations as LAT and is identical in meaning. LANDLAT is the item used by noun 89 to display landmark latitude.

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[ ] Added GSOP # R-577 PCR # 237 Rev. 2 Date 8/1/68

Word Number	Contents
53	LANDMARK LONGITUDE is the longitude of the landmark which P22 is updating, scaled degrees/360. The range of values is $-.5$ revolutions $\leq$ LONG $< .5$ revolutions. It may be either earth-centered or moon-centered. If, upon entry of P22, CMOONFLG (Flagword 8, bit 12) equals zero, the coordinate system is earth-centered. Conversely, the coordinate system will be moon-centered if CMOONFLG equals one. The longitude is computed for known landmarks only at the start of P22. At the completion of P22, the longitude is computed for all landmarks and contains the updated value.
54	LANDMARK ALTITUDE is the altitude of the landmark above the Fischer Ellipsoid for earth orbit and above the mean lunar radius for moon orbit, scaled meters/2^{29}. Tested values have varied between +2000 to -2000 meters. It may be either earth-centered or moon-centered. If, upon entry of P22, CMOONFLG (Flagword 8, bit 12) equal zero, the coordinate system is earth-centered. Conversely, the coordinate system will be moon-centered if CMOONFLG equals one. The altitude is computed for known landmarks only at the start of P22. At the completion of P22, the altitude is computed for all landmarks and contains the updated value.
55-58	SPARES. Same description as word 31 of the Powered List.
59-73	Same as words 59-73 on the Powered List.
74a	The number of valid Landing site marks, from one to five, which are stored in the SVMRKDAT table, scaled 2^{-14}. This item is computed by R53 and left in QPRET. P22 moves it from QPRET to 8NN. This quantity is computed once per operation of P22 and does not change.
74b	Garbage. This register is used by S22LOC which indicates the address, within the SVMRKDAT table, of the present set of mark data.
75	Same as word 77 of the Powered List.
76-78	LUNAR LANDING SITE POSITION VECTOR (X, Y, Z) measured in moon-fixed coordinates from the center of the moon to the surface of the moon at the landing site, scaled meters/2^{27}. It is used in lunar orbits only and must be selected by the astronaut using nouns 70 or 71. If selected by the astronaut, it is used at the start of P22 to compute the initial landmark vector ($\underline{R}_L$) and then updated at the end of P22 as a result of data computed from the results of astronaut-acquired sighting marks.

Word Number	Contents
79	SPARE. Same description as word 31 of the Powered List.
80-94	Same as words 80-94 of the Powered List.
95-100	Spares. Same description as word 31 of the Powered List.

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North American Rockwell, Inc.
Space and Information Systems Division
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NASA/RASPO GAEC
National Aeronautics and Space Administration
Resident Apollo Spacecraft Program Officer
Grumman Aircraft Engineering Corporation
Bethpage, Long Island, New York
(1)

NASA/RASPO ACED
National Aeronautics and Space Administration
Resident Apollo Spacecraft Program Officer
AC Electronics Division
General Motors Corporation
Milwaukee, Wisconsin 53201
Attn: Mr. W. Swingle
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Washington, D.C. 20036
Attn: Info. Analysis Section
(6)

LINK:
LINK Group, GPSI SIMCOM
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Houston, Texas 77058
Attn: Mr. D. Klingbell
(3)

TRW:
Gilbert H. Friedman
Building 82 Rm 2067
TRW System Group
One Space Park
Redondo Beach, California 90278
(5)