

LISTA ÖVER KOMPATIBLA REGLAGE

Mars 2026



Saknas ditt reglage i listan? **FRÅGA OSS!**

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Glossary

Control mode

SS – Single-step control

Forward / Neutral / Reverse only. No RPM control.

DS – Dual-step control

Two predefined RPM levels per direction.

PR – Proportional control

Continuous RPM control within a defined operating range.

Proportional control modes

Stepped – RPM adjusted in discrete steps.

Continuous – Smooth continuous RPM adjustment.

Station activation from remote

The remote can activate the engine control system, taking control if required.

Active station feedback

The remote indicates whether Shipcontroller currently has engine control.

OEM interface required

A manufacturer-specific gateway or interface is required.

Supported remotes

Compatible Shipcontroller remote models.

Control system	CUMMINS (Glendinning CC1)
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Control head



<i>Shipcontroller controller</i>	EA-GSA2
<i>Control mode</i>	PR – Proportional
<i>Station activation from remote</i>	Yes
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	None
<i>Supported remotes</i>	DockerOne: DS DockerPro: Proportional (stepped) EzVector: Proportional (stepped or continuous)

Control system	Glendinning CC1 / CC2
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Control head



<i>Shipcontroller controller</i>	EA-GSA2
<i>Control mode</i>	PR – Proportional
<i>Station activation from remote</i>	Yes
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	None
<i>Supported remotes</i>	DockerOne: DS DockerPro: Proportional (stepped) EzVector: Proportional (stepped or continuous)

Control system **MTU Blue Vision**

Control head



<i>Shipcontroller controller</i>	EA-MTU-BV
<i>Control mode</i>	SS
<i>Station activation from remote</i>	Yes
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	None
<i>Supported remotes</i>	DockerOne: SS DockerPro: SS EzVector: SS

Control system **MAN - REXROTH/EMERSON (CANbus versions 5-pin)**

Control head



<i>Shipcontroller controller</i>	EA-MANRX
<i>Control mode</i>	SS
<i>Station activation from remote</i>	Yes
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	None
<i>Supported remotes</i>	DockerOne: SS DockerPro: SS EzVector: SS

Control system	Minimarex-C (12 pin connector)
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Control head



<i>Shipcontroller controller</i>	EA-MNMRX12P-PR
<i>Control mode</i>	PR
<i>Station activation from remote</i>	Yes
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	None
<i>Supported remotes</i>	DockerOne: DS DockerPro: Proportional (stepped) EzVector: Proportional (stepped or continuous)

Control system	Flexball / Bellmarine (0-5V analog control for electric drives)
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Control head



<i>Shipcontroller controller</i>	CNCV1PISOv11
<i>Control mode</i>	PR
<i>Station activation from remote</i>	Yes
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	None
<i>Supported remotes</i>	DockerPro: Proportional (stepped) EzVector: Proportional (stepped or continuous)

Control system	TWIN DISC EC200
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Control head



<i>Shipcontroller controller</i>	EA-EC200P
<i>Control mode</i>	PR – Proportional engine control Includes Intelligent Idle Mode control
<i>Station activation from remote</i>	Yes
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	None
<i>Supported remotes</i>	DockerPro: Proportional (stepped) EzVector: Proportional (stepped or continuous)

Control system	Vetus EC4
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Control head



<i>Shipcontroller controller</i>	EA-VTSEC4
<i>Control mode</i>	PR – Proportional
<i>Station activation from remote</i>	Yes
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	None
<i>Supported remotes</i>	DockerOne: DS DockerPro: Proportional (stepped) EzVector: Proportional (stepped or continuous)

Control system	VOLVO EDC, EVC-C
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Control head



<i>Shipcontroller controller</i>	EA-VPANLG
<i>Control mode</i>	DS
<i>Station activation from remote</i>	Available depending on Volvo system version
<i>Active station feedback</i>	Available depending on Volvo system version
<i>OEM interface required</i>	None
<i>Supported remotes</i>	DockerOne: DS DockerPro: DS EzVector: DS

Control system	VOLVO EVC-E4, EVC2.0
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Control head



<i>Shipcontroller controller</i>	EA-VPTJS
<i>Control mode</i>	PR – Proportional
<i>Station activation from remote</i>	No – The vessel control station must be active
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	VP TJS Interface
<i>Supported remotes</i>	DockerOne: DS DockerPro: Proportional (stepped) EzVector: Proportional (stepped or continuous)

Control system VOLVO JOYSTICK SYSTEM / VOLVO IPS (Old version)

Control head



<i>Shipcontroller controller</i>	EA-VPX8-DT
<i>Control mode</i>	X/Y axes: Proportional Z axis: Stepped (user adjustable)
<i>Station activation from remote</i>	Joystick activation and mode selection The vessel control station must be active
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	None
<i>Supported remotes</i>	EzVector (IPS version)

Control system VOLVO JOYSTICK SYSTEM / VOLVO IPS (Modern version)

Control head



<i>Shipcontroller controller</i>	EA-VPX8-MLX
<i>Control mode</i>	X/Y axes: Proportional Z axis: Stepped (user adjustable)
<i>Station activation from remote</i>	Joystick activation and mode selection. The vessel control station must be active
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	None
<i>Supported remotes</i>	EzVector (IPS version)

Note: Volvo EVC2.0 and later versions display a system warning when an external controller is detected. The system continues to operate normally, but this warning may be undesirable for some users.

Control system **FLEXBALL 3500/4200/4500 series, WR CONTROLS**

Control head



<i>Shipcontroller controller</i>	EA-VTSEC4
<i>Control mode</i>	PR – Proportional
<i>Station activation from remote</i>	Yes
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	None
<i>Supported remotes</i>	DockerOne: DS DockerPro: Proportional (stepped) EzVector: Proportional (stepped or continuous)

Control system **YANMAR VC10**

Control head



<i>Shipcontroller controller</i>	EA-YNMRVC10
<i>Control mode</i>	DS
<i>Station activation from remote</i>	Yes
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	Yes - VC10 control kit required per engine
<i>Supported remotes</i>	DockerOne: DS DockerPro: DS EzVector: DS

Control system **YANMAR VC20**

Control head



<i>Shipcontroller controller</i>	EA-YNMRVC20P
<i>Control mode</i>	PR – Proportional
<i>Station activation from remote</i>	Yes
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	Yes - VC20 control kit required
<i>Supported remotes</i>	DockerOne: DS DockerPro: Proportional (stepped) EzVector: Proportional (stepped or continuous)

Control system **ZF Smartcommand**

Control head



<i>Shipcontroller controller</i>	EA-ZFSMC
<i>Control mode</i>	PR – Proportional
<i>Station activation from remote</i>	Yes
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	None
<i>Supported remotes</i>	DockerOne: DS DockerPro: Proportional (stepped) EzVector: Proportional (stepped or continuous)

Control system	ZF Microcommander, ClearCommand, CruiseCommand, MS series
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Control head



<i>Shipcontroller controller</i>	EA-ZFMCC
<i>Control mode</i>	DS
<i>Station activation from remote</i>	Yes
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	None
<i>Supported remotes</i>	DockerOne: DS DockerPro: DS EzVector: DS

Control system	SUZUKI Precision Control
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Control head



<i>Shipcontroller controller</i>	EA-SZKPC1
<i>Control mode</i>	DS
<i>Station activation from remote</i>	No – The vessel control station must be active
<i>Active station feedback</i>	No
<i>OEM interface required</i>	None
<i>Supported remotes</i>	DockerOne: DS DockerPro: DS EzVector: DS

Control system **NHK MEC KHxx**

Control head



<i>Shipcontroller controller</i>	EA-NHKMEC-KE
<i>Control mode</i>	DS
<i>Station activation from remote</i>	Yes
<i>Active station feedback</i>	Yes
<i>OEM interface required</i>	None
<i>Supported remotes</i>	DockerOne: DS DockerPro: Proportional (stepped) EzVector: Proportional (stepped or continuous)

Thruster System Compatibility Guide

Thruster system

Shipcontroller integrated on/off thruster control



All Shipcontroller systems include an SMCU unit with dry relay contacts for:

- Bow thruster control
- Stern thruster control
- Thruster enable

These outputs can be used to control most on/off thruster systems.

The thruster enable output includes a timed function to control thruster systems that require an enable signal before use.

<i>Shipcontroller controller</i>	SMCU
<i>Control mode</i>	On/Off
<i>Thruster activation from the remote</i>	Yes – automatic (on first thruster command). The thruster enable relay is activated on the first command and includes an internal timeout.
<i>Thruster deactivation</i>	Automatic after an inactivity timeout or when the remote is switched off.
<i>OEM interface required</i>	None
<i>Number of thrusters supported</i>	2 (bow and stern)
<i>Compatible Shipcontroller remote models – control modes</i>	DockerOne: fixed thrust control (on/off) DockerPro: fixed thrust control (PTH, DobleClic) EzVector: fixed thrust control (PTH, DobleClic)
<i>Shipcontroller DPS suitability</i>	Limited suitability. In general, on/off thrusters are not well suited for dynamic positioning, except for hydraulic thrusters, which allow extended duty cycles. Long-cycle PWM control (Shipcontroller PTH function) improves the usability of on/off thrusters in DPS applications.

Thruster system

ABT-TRAC proportional thrusters



ABT-TRAC TRACLINK thrusters

<i>Shipcontroller controller</i>	IFTH-ABTTRACLINK
<i>Control mode</i>	PR – Proportional
<i>Thruster activation from the remote</i>	Yes – automatic (on first thruster command)
<i>Thruster deactivation</i>	Automatic after inactivity timeout or when the remote is switched off.
<i>OEM interface required</i>	None
<i>Number of thrusters supported</i>	Up to 4 thrusters
<i>Compatible Shipcontroller remote models – control modes</i>	DockerOne: fixed thrust control $\pm 100\%$ DockerPro: proportional stepped control (PTH, DobleClic). EzVector: proportional stepped or continuous control (PTH, DobleClic).
<i>Shipcontroller DPS suitability</i>	High – subject to thruster model, vessel characteristics and duty cycle.

Thruster system

SLEIPNER S-LINK proportional thrusters



All Sleipner S-LINK proportional thrusters, including hydraulic, electric and retractable.

<i>Shipcontroller controller</i>	IFTH-SLINK
<i>Control mode</i>	PR – Proportional
<i>Thruster activation from the remote</i>	Yes – automatic (on first thruster command)
<i>Thruster deactivation</i>	Automatic after inactivity timeout or when the remote is switched off.
<i>OEM interface required</i>	Sleipner GW-1
<i>Number of thrusters supported</i>	Up to 4 thrusters
<i>Compatible Shipcontroller remote models – control modes</i>	DockerOne: fixed thrust control $\pm 100\%$ DockerPro: proportional stepped control (PTH, DobleClic). EzVector: proportional stepped or continuous control (PTH, DobleClic).
<i>Shipcontroller DPS suitability</i>	High – subject to thruster model, vessel characteristics and duty cycle.

Thruster system

VETUS V-CAN proportional thrusters



All Vetus BOWPRO proportional thrusters

<i>Shipcontroller controller</i>	IFTH-VCAN
<i>Control mode</i>	PR – Proportional
<i>Thruster activation from the remote</i>	Yes – automatic (on first thruster command)
<i>Thruster deactivation</i>	Automatic after inactivity timeout or when the remote is switched off.
<i>OEM interface required</i>	None
<i>Number of thrusters supported</i>	Up to 4 thrusters
<i>Compatible Shipcontroller remote models – control modes</i>	DockerOne: fixed thrust control $\pm 100\%$ DockerPro: proportional stepped control (PTH, DobleClic). EzVector: proportional stepped or continuous control (PTH, DobleClic).
<i>Shipcontroller DPS suitability</i>	High – subject to thruster model, vessel characteristics and duty cycle.

Thruster system **QUICK AMC SYSTEM thrusters**



All Quick thrusters controlled via the AMC system

<i>Shipcontroller controller</i>	IFTH-QUICKAMC
<i>Control mode</i>	PR – Proportional
<i>Thruster activation from the remote</i>	Yes – automatic (on first thruster command)
<i>Thruster deactivation</i>	Automatic after inactivity timeout or when the remote is switched off.
<i>OEM interface required</i>	Quick AMC controller
<i>Number of thrusters supported</i>	Up to 2 thrusters
<i>Compatible Shipcontroller remote models – control modes</i>	DockerOne: fixed thrust control $\pm 100\%$ DockerPro: proportional stepped control (PTH, DobleClic). EzVector: proportional stepped or continuous control (PTH, DobleClic).
<i>Shipcontroller DPS suitability</i>	High – subject to thruster model, vessel characteristics and duty cycle.

Thruster system **QUICK TCD On/Off thrusters**



On/Off retractable and fixed thrusters commanded by TCD series control panels.

<i>Shipcontroller controller</i>	None
<i>Control mode</i>	On/Off
<i>Thruster activation from the remote</i>	Yes – automatic (on first thruster command)
<i>Thruster deactivation</i>	Automatic after inactivity timeout or when the remote is switched off.
<i>OEM interface required</i>	Quick TTA 12V or 24V
<i>Number of thrusters supported</i>	Each thruster requires an OEM interface
<i>Compatible Shipcontroller remote models – control modes</i>	DockerOne: fixed thrust control $\pm 100\%$ DockerPro: fixed thrust control (PTH, DobleClic) EzVector: fixed thrust control (PTH, DobleClic)
<i>Shipcontroller DPS suitability</i>	Limited suitability.

Thruster system

QUICK NGC-T thrusters
Preliminary – availability to be confirmed



<i>Shipcontroller controller</i>	IFTH-QUICKNGCT
<i>Control mode</i>	PR – Proportional
<i>Thruster activation from the remote</i>	Yes – automatic (on first thruster command)
<i>Thruster deactivation</i>	Automatic after inactivity timeout or when the remote is switched off.
<i>OEM interface required</i>	Quick NGC-T
<i>Number of thrusters supported</i>	Up to 4 thrusters
<i>Compatible Shipcontroller remote models – control modes</i>	DockerOne: fixed thrust control $\pm 100\%$ DockerPro: proportional stepped control (PTH, DobleClic). EzVector: proportional stepped or continuous control (PTH, DobleClic).
<i>Shipcontroller DPS suitability</i>	High – subject to thruster model, vessel characteristics and duty cycle.

Thruster system

QS-SEAMASTER
Preliminary – availability to be confirmed



<i>Shipcontroller controller</i>	IFTH-QUICKNGCT
<i>Control mode</i>	PR – Proportional
<i>Thruster activation from the remote</i>	Yes – automatic (on first thruster command)
<i>Thruster deactivation</i>	Automatic after inactivity timeout or when the remote is switched off.
<i>OEM interface required</i>	QS Seamaster NGC-T
<i>Number of thrusters supported</i>	2
<i>Compatible Shipcontroller remote models – control modes</i>	DockerOne: fixed thrust control $\pm 100\%$ DockerPro: proportional stepped control (PTH, DobleClic). EzVector: proportional stepped or continuous control (PTH, DobleClic).
<i>Shipcontroller DPS suitability</i>	High – subject to thruster model, vessel characteristics and duty cycle.

Thruster system

DANFOSS PVREL



All hydraulic thrusters controlled by PVREL controls and hydraulic valves using voltage control, 12 or 24V.

<i>Shipcontroller controller</i>	IFTH-DNFSPVREL
<i>Control mode</i>	PR – Proportional, voltage control.
<i>Thruster activation from the remote</i>	No. Thrusters must be activated by the user before using the remote.
<i>Thruster deactivation</i>	Manual. Priority is managed by Shipcontroller, giving precedence to the vessel controls (the vessel joystick overrides the remote).
<i>OEM interface required</i>	None
<i>Number of thrusters supported</i>	1 thruster per controller module
<i>Compatible Shipcontroller remote models – control modes</i>	DockerOne: fixed thrust control $\pm 100\%$ DockerPro: proportional stepped control (PTH, DobleClic). EzVector: proportional stepped or continuous control (PTH, DobleClic).
<i>Shipcontroller DPS suitability</i>	High – subject to thruster model, vessel characteristics and duty cycle.

Thruster system

MAX-POWER ECO Proportional thrusters
Preliminary – availability to be confirmed



All ECO or ECO retractable proportional thrusters.

<i>Shipcontroller controller</i>	IFTH-MXPWR-ECO
<i>Control mode</i>	PR – Proportional
<i>Thruster activation from the remote</i>	Yes – automatic (on first thruster command)
<i>Thruster deactivation</i>	Automatic after inactivity timeout or when the remote is switched off.
<i>OEM interface required</i>	None
<i>Number of thrusters supported</i>	One per controller
<i>Compatible Shipcontroller remote models – control modes</i>	DockerOne: fixed thrust control $\pm 100\%$ DockerPro: proportional stepped control (PTH, DobleClic). EzVector: proportional stepped or continuous control (PTH, DobleClic).
<i>Shipcontroller DPS suitability</i>	High – subject to thruster model, vessel characteristics and duty cycle.

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