R-Pilot

Guidance to proponents on preparing for the technology readiness assessment

November 2025

PART 1: TRAINING AND FAMILIARISATION

	1	2
	Prerequisites for system users	How the pre-requisites would be achieved from the perspective of the manufacturer or system integrators
	What training and familiarisation with the system would be required for maritime pilots to achieve error-free operation, and how is this delivered?	
:	What training and familiarisation with the system would be required for the Master and bridge team to achieve error-free operation, and how is this delivered?	

PART 2: PILOT ASSIGNMENT AND RECORD KEEPING

	1	2	3	4
	Claim (Pilotage workflow task)	Argument (How does the solution enable the workflow task? What information from Appendix 1 is provided?)	Evidence (What evidence is presented to justify the argument that the solution can deliver the workflow task? What assumptions are made? How is the relevant information from Appendix 1 provided?)	Dependencies and Assumptions (What information, data or services are required? What assumptions are made about the sources of this information?)
3	The solution provides a secure means of assigning a remote pilot to a ship.			
4	The solution is scalable, allowing multiple ships to comply with mandatory pilotage requirements simultaneously.			
5	The solution has a means of recording and retaining complete records of all communications between a remote pilot and the master and bridge team.			

PART 3: EXECUTION OF PILOTAGE

	1	2	3	4
	Claim (Pilotage workflow task)	Argument (How does the solution enable the workflow task? What information from Appendix 1 is provided?)	Evidence (What evidence is presented to justify the argument that the solution can deliver the workflow task? What assumptions are made? How is the relevant information from Appendix 1 provided?)	Dependencies and Assumptions (What information, data or services are required? What assumptions are made about the sources of this information?)
	The solution enables a continuous Master-Pilot			
6	information exchange (MPX) under all operational			
	conditions, including during emergencies.			
7	The pilot can direct the safe navigation of the ship under all operational conditions, including during emergencies.			
	The pilot can give helm, engine and thruster orders and			
8	verify they are executed correctly by the bridge team.			
	The pilot can perceive, comprehend and act on the			
9	position of the ship relative to the planned track, aids to			
	navigation and proximate navigation hazards.			
	The pilot can perceive, comprehend, and act on safe			
10	speed in prevailing circumstances and conditions, and in			
	accordance with local regulations.			
	The pilot can perceive and comprehend developing			
11	traffic situations, including arrangements for meeting			
' '	and overtaking in narrow channels, and act in			
-	accordance with COLREGs or local regulations.			
12	The pilot can perceive, comprehend and act on the			
	weather at or in the vicinity of the ship.			

	1	2	3	4
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13	The pilot can perceive, comprehend and act on predicted and actual under-keel clearance, including at the berth, and in compliance with local regulations.			
14	The pilot can perceive, comprehend and act on the interaction between ships passing at close quarters and maintain safe distances from other ships and infrastructure.			
15	The pilot can perceive, comprehend and act on shallow water and bank effects in narrow channels, rivers, canals and locks.			
16	The pilot can perceive, comprehend and act on the effects of wind and/or tide on the set and drift of the ship.			
17	The pilot can perceive, comprehend and act on any increase in draft due to heeling in a turn.			
18	The pilot can perceive, comprehend and act on the progress of a turn and heading leaving a turn.			
19	The pilot can coordinate escort tugs, if required.			
20	The pilot can perceive, comprehend and act on the wake being generated by the ship and its impact on other ships and the environment, including compliance with local regulations.			

PART 4: EXECUTION OF DOCKING AND UNDOCKING (AT BERTH OR IN LOCKS)¹ AND ANCHORING

	1	2	3	4
	Claim (Pilotage workflow task)	Argument (How does the solution enable the workflow task? What information from Appendix 1 is provided?)	Evidence (What evidence is presented to justify the argument that the solution can deliver the workflow task? What assumptions are made? How is the relevant information from Appendix 1 provided?)	Dependencies and Assumptions (What information, data or services are required? What assumptions are made about the sources of this information?)
21	The pilot can direct the casting off sequence of lines to shipboard personnel and mooring personnel ashore.			
22	The pilot can perceive, comprehend and act on the position of mooring boats.			
23	The pilot can direct (un)docking and anchoring manoeuvres by providing helm, engine and thruster orders to the Master and bridge team.			
24	The pilot can coordinate tugs during (un)docking manoeuvres.			
25	The pilot can verify that the helm, engine and thruster orders are executed correctly.			
26	The pilot can perceive, comprehend and act on the position of the ship relative to the berth and the final position of the bridge.			
27	The pilot can perceive, comprehend, and act on the presence of obstructions, including overhangs and dock cranes.			
28	The pilot can receive information on propeller and thruster clearance.			
29	The pilot can perceive, comprehend and act on the lead of the anchor chain.			

¹ Tasks are in chronological order for undocking and may be in a different order for docking.

	1	2	3	4
	Claim (Pilotage workflow task)	Argument (How does the solution enable the workflow task? What information from Appendix 1 is provided?)	Evidence (What evidence is presented to justify the argument that the solution can deliver the workflow task? What assumptions are made? How is the relevant information from Appendix 1 provided?)	(What information, data or services are required? What
30	The pilot can determine and verify the length of the anchor chain paid out.			

PART 5: DATA FOR NAVIGATION

	1	2	3	4
	Claim (Pilotage workflow task)	Argument (How does the solution enable the workflow task? What information from Appendix 1 is provided?)	Evidence (What evidence is presented to justify the argument that the solution can deliver the workflow task? What assumptions are made? How is the relevant information from Appendix 1 provided?)	Dependencies and Assumptions (What information, data or services are required? What assumptions are made about the sources of this information?)
31	The pilot can independently make use of visual Aids to Navigation to determine the ship's position.			
32	The pilot can independently use X-band and/or S-band radar to determine the ship's position and the position of other objects.			
33	The pilot can know X- and S-band radar settings and errors.			
34	The pilot can independently use shipboard electronic position fixing systems (EPFS) or an alternative source to plot the position and movement of a ship on ECDIS.			
35	The pilot can use real-time kinematics (RTK), which is independent of the shipboard sensors required by SOLAS Chapter V, when necessary, given the characteristics of the ship and the situation dictates.			
36	The pilot can know ship's true heading and determine or verify gyro error.			
37	The pilot can know ship's course over ground.			
38	The pilot can know ship's speed through water, speed over ground.			
39	The pilot can know depth beneath the keel at the ship's position.			
40	The pilot can know the ship's rudder, or equivalent steering arrangement position.			
41	The pilot can know ship's telegraph, or equivalent engine control settings.			
42	The pilot can independently interrogate the ship's Automatic Identification System (AIS) or obtain AIS data from an alternative source.			
43	The pilot can know the AIS antenna offset, if applicable.			

PART 6: CONNECTIVITY AND COMMUNICATIONS (INCLUDING (UN)DOCKING AT BERTH OR IN LOCKS)

	1	2	3	4
	Claim (Pilotage workflow task)	Argument (How does the solution enable the workflow task? What information from Appendix 1 is provided?)	Evidence (What evidence is presented to justify the argument that the solution can deliver the workflow task? What assumptions are made? How is the relevant information from Appendix 1 provided?)	assumptions are made about the sources of this
44	The pilot can establish and maintain secure connectivity with the ship, or an alternative source, to receive the data in Parts 4 and 5.			

	1	2	3	4
	Claim (Pilotage workflow task)	Argument (How does the solution enable the workflow task? What information from Appendix 1 is provided?)	Evidence (What evidence is presented to justify the argument that the solution can deliver the workflow task? What assumptions are made? How is the relevant information from Appendix 1 provided?)	Dependencies and Assumptions (What information, data or services are required? What assumptions are made about the sources of this information?)
45	Hardware required to be installed onboard conforms to applicable IMO, ISO/IEC and IACS standards for electromagnetic compatibility			
46	Hardware required to be installed onboard and integrate with the equipment required by SOLAS chapter V conforms with the applicable ISO/IEC standard for data exchange			
47	The pilot can establish and maintain connectivity with the ship, or an alternative source, to receive the data in Parts 4 and 5 using reversionary means.			
48	The pilot can establish and maintain secure two-way communications with the master and bridge team.			
49	The pilot can establish and maintain secure two-way communications with the master and bridge team using reversionary means.			
50	The pilot and the master and bridge team can conduct closed-loop communications throughout the act of pilotage.			
51	The pilot can independently establish two-way communications with Vessel Traffic Services.			
52	The pilot can comply with ship reporting scheme obligations throughout the act of pilotage.			
53	The pilot can independently establish two-way communications with tugs required for escorting or manoeuvring the ship throughout the act of pilotage.			
54	The pilot can conduct closed-loop communications with the Masters of escort or harbour tugs throughout the act of pilotage.			
55	The pilot can independently establish two-way communications with other ships (including to coordinate collision avoidance and ships meeting) and other waterway users, as required, throughout the act of pilotage.			
56	The pilot can independently establish two-way communications with mooring personnel during docking and undocking.			
57	The pilot can conduct closed-loop communications with mooring personnel during (un)docking operations.			

APPENDIX 1: LATENCY

This appendix provides information on the recommended maximum latency of information exchange between the data source and the pilot.

	Information	Latency Identifier*
1	Two-way communications between the pilot and the master, and bridge team	U
2	Day/night optics at least equivalent to the bridge visibility requirements of SOLAS regulation V/22	U
3	Day/night optics with zoom	U
4	Processed radar data	U
5	Raw radar data	U
6	Radar control (gain, clutter, rain, pulse length) and tools (EBL, VRM, PI)	U
7	True heading from a gyro compass or transmitting heading device (THD)	U
8	Rate of turn indicator (ROTI)	U
9	Rudder angle indicator (RAI)	U
10	Thruster(s) settings	U
11	Ship position by Global Navigation Satellite Service (GNSS)	U
12	Course Over Ground	U
13	Speed Over Ground	U
14	Position of the ship relative to the planned track and navigational hazards	U
15	Real Time Kinematics	U
16	Sound signals (COLREGs)	U
17	Sound signals from other ship and aids to navigation	U
18	Bridge communications and exchanges between the master and bridge team	U
19	Ship-to-ship, Ship-to-shore and shore-to-ship communications (VHF)	U
20	Night/day ship-to-ship signals	U
21	Depth beneath the keel	L
22	Magnetic compass	L
23	Wind speed & direction	L
24	Automatic Identification System (AIS)	L
25	Inclinometer	L
26	Telegraph Settings, Engine RPM or Propeller Pitch	L
27	External data (e.g. weather sensors, live tidal data)	L

*Expected latency levels:

Description	Maximum Latency	Identifier	
Ultra Low Latency	200 milliseconds	U	
Low Latency	5 seconds	L	
Acceptable Latency	30 seconds	Α	