

Panasonic

Requirements

- Robotic Camera System Interface Software Option
- Serial Interface Cable (DB9 to DB9)
- Control DeviceMaster or Sealevel SeaLINK
- Ethernet Cable

Port Connections

Communications			
Robotic Camera RS-422	>	DeviceMaster or SeaLINK RS-422	
DeviceMaster or SeaLINK Ethernet	>	Local Area Network Ethernet	
Robotic Camera Ethernet	>	Local Area Network Ethernet	

Video			
Switcher Input BNC	>	Robotic Camera Video Out BNC	

For More Information on...

- configuring switcher inputs, refer to the *Caprica User Guide*.

Serial Interface Cable Pinouts

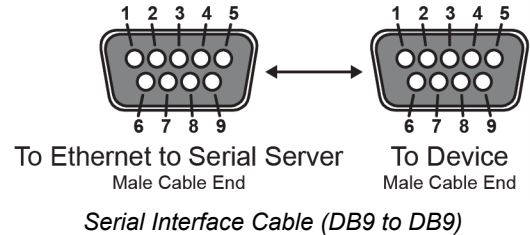
A Panasonic robotic camera can connect to your Caprica Server through a controller or directly from the camera head.

Controller

The DeviceMaster and the SeaLINK Ethernet to serial servers both use the following serial interface cable pinouts to connect to a Panasonic robotic camera controller:

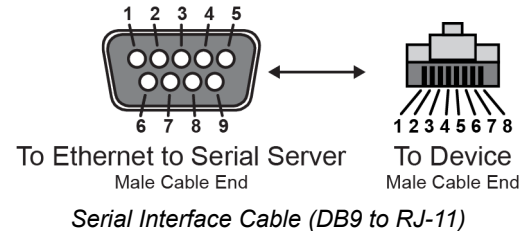
DeviceMaster		Panasonic Controller	
Pin	Signal	Pin	Signal
3	Tx	>	2 Rx
2	Rs	>	3 Tx
5	Ground	>	5 Ground

- ★ When using a SeaLINK Ethernet to serial server in your OverDrive system, terminate any control signals that are not going to be used. The most common way to do this is connect RTS to CTS and RI. Also, connect DCD to DTR and DSR.



DeviceMaster to Camera Head

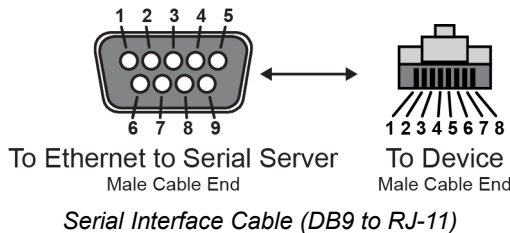
DeviceMaster		Panasonic Camera Head	
Pin	Signal	Pin	Signal
2	RxA (Rx-)	>	4 TxA (Tx-)
7	TxB (Tx+)	>	6 RxB (Rx+)
8	RxB (Rx+)	>	5 TxB (Tx+)
3	TxA (Tx-)	>	3 RxA (Rx-)



SeaLINK to Camera Head

SeaLINK		Panasonic Camera Head	
Pin	Signal	Pin	Signal
2	RxA (Rx-)	>	4 TxA (Tx-)
4	TxB (Tx+)	>	6 RxB (Rx+)
1	RxB (Rx+)	>	5 TxB (Tx+)
3	TxA (Tx-)	>	3 RxA (Rx-)

- ★ When using a SeaLINK Ethernet to serial server in your OverDrive system, terminate any control signals that are not going to be used. The most common way to do this is connect RTS to CTS, connect positive to positive and negative to negative.



Configuring the Ethernet to Serial Server

The Ethernet to serial server in an OverDrive system handles the communication between your Panasonic robotic camera and Caprica Server. OverDrive systems can contain a DeviceMaster or SeaLINK Ethernet to serial server. Use one of the following sections to configure the Ethernet to serial server in your OverDrive System:

- “**DeviceMaster**” on page 4–2
- “**SeaLINK**” on page 4–2

DeviceMaster

A Panasonic robotic camera connects to a serial port on the DeviceMaster. Use the following procedure to configure the DeviceMaster for your Panasonic robotic camera:

1. Use a web browser to open the **Server Status** web page for your DeviceMaster. The default IP address for a DeviceMaster is 192.168.250.250.
The **Server Status** web page opens in the web browser.
2. Click **Port #** link, where # is the port number on the DeviceMaster to which you connect your Panasonic robotic camera.
The **Edit Port # Configuration** web page opens for the selected port.
3. In the **Port Name** box, enter *Shotoku*.
4. In the **Serial Configuration** section, use the **Mode** list to select **RS-422**.
5. Use the **Baud** list to select **38400**.
6. Use the **Parity** list to select **odd**.
7. Use the **Data Bits** list to select **8**.
8. Use the **Stop Bits** list to select **1**.
9. Use the **DTR** list to select **off**.
10. Use the **EOL** list to select **disabled**.

11. In the **TCP Connection Configuration** section, select the **Enable** check box.
12. Select the **Listen** check box.
13. In the **Port** box, enter the port number that the DeviceMaster uses to listen for communication from a Panasonic robotic camera.
14. Click **Save**.
The **Port Configuration Updated** web page opens.
15. Click **OK**.
The **Server Status** web page opens.
16. Click **Reboot**.
The DeviceMaster reboots with the new configuration.

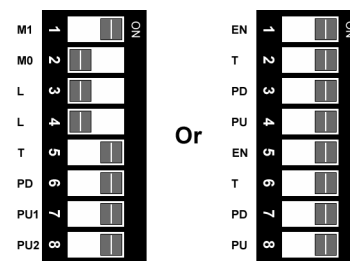
SeaLINK

A Panasonic robotic camera connects to a serial port on the SeaLINK. You must configure the connected SeaLINK serial port to communicate with a Panasonic robotic camera.

Hardware Configuration

The SeaLINK Ethernet to serial server is primarily configured using the web interface. Before using the web interface, the SeaLINK DB9 port that connects a Panasonic robotic camera to your OverDrive system requires DIP Switch configuration.

Inside the SeaLINK each DB9 serial port has a set of eight DIP Switches. To communicate with a Panasonic robotic camera the RS Mode of the DB 9 serial port that connects a Panasonic robotic camera must be set to RS-422. Set the DIP Switches associated with the connected port as follows:



DB9 DIP Switch Settings for RS-422

For More Information on...

- configuring the DIP Switches for SeaLINK DB9 ports, refer to the **Hardware Configuration** section in the *SeaLINK User Manual | Ethernet Serial Server Family*.

Web Interface Configuration

After setting the DIP Switches associated with the DB9 port on the SeaLINK used to connect a Panasonic robotic camera, you can use the SeaLINK web interface to complete the SeaLINK configuration.

Use the following procedure to configure the SeaLINK for your Panasonic robotic camera:

1. Use a web browser to open the **Summary** web page for your SeaLINK. The URL of the Summary web page is the IP address of the SeaLINK.
The **Summary** web page opens in the web browser.
 2. Click the **Port Settings** tab.
The **Port Settings** web page opens.
 3. In the **Port # Defaults Section** section, where # is the port number on the SeaLINK to which you connect your Panasonic robotic camera, enter 38400 in the **Baud Rate** box.
 4. Use the **Data Bits** list to select **8**.
 5. Use the **Stop Bits** list to select **1**.
 6. Use the **Parity** list to select **Odd**.
 7. Use the **Flow Control** list to select **None**.
 8. Use the **RS Mode** list to select **RS 422/488**.
 9. Use the **Protocol** list to select **Ignored**.
 10. Click **Submit**.
 11. Click the **Administration** tab.
The **Administration** web page opens.
- ★ Values set for settings on the **Administration** web page are set for all SeaLINK serial ports.
12. In the **General Settings** section, enter a name to identify the SeaLINK in the **Name** box.
 13. Use the **Connection Protocol** list to select **Raw Data**.
 14. At the bottom of the **Administration** web page, select the **Reboot** check box.
 15. Click **Submit**.
The SeaLINK reboots with the new configuration.

Remote Device Port Configuration Settings

Use the following procedure to configure a remote device for your Panasonic robotic camera on the Caprica Server:

1. Use the current version of **DashBoard** software to connect to your **Caprica Server**.
2. In the **DashBoard Tree View**, double-click the **Port Configuration** node of your Caprica Server.
3. In the **Port Configuration Summary** table, double-click a **REMOTE#** port in the **Port** column.
4. In the **Configure REMOTE#** panel, click **Robotic CAM**.
5. Click **Panasonic**.
6. Click **Network Settings**.

7. Use the following settings to configure the **Network Settings** for your Panasonic robotic camera:

- **Ethernet Role** — Client
- **Remote IP Address** — IP address of the Ethernet to serial server in your OverDrive system
- **Remote Port** — Port number on the Ethernet to serial server to which you connect your Panasonic robotic camera.

When using a SeaLINK Ethernet to serial server in your OverDrive system the Remote Port number is associated with the SeaLINK serial port number to which you connected your Panasonic robotic camera. The SeaLINK serial port to Remote Port associations are as follows:

SeaLINK Serial Port	Remote Port
1	4680
2	4681
3	4682
4	4683

- **Local IP Address** — 0.0.0.0
- **Local Port** — 0
- **Protocol** — TCP

8. Click **Apply Changes** to save the network settings.

Device Settings

Use the following procedure to configure the device settings for your Panasonic robotic camera on the Caprica Server:

1. Click **Device Settings**.
2. Click the **Device** setting button to select the camera head model to control.
3. Click the **Controller** setting button to select the controller used with the selected camera head.
4. Use the **CmdDelay** setting to enter or select the delay time between messages.
When **TuningS** is the selected Controller, enter **0** for this setting.
5. Use the **Cam Reselect** setting to control reselecting the camera.
 - **OFF** — do not reselect the camera.
 - **ON** — force reselecting the camera after operations.
 When **TuningS** is the selected Controller, select **OFF** for this setting.

- Use the **Toggle Cam** setting to control camera selection.
 - OFF** — do not force select a camera before switching.
 - ON** — force selecting a different camera before selecting a camera to ensure the switch between cameras.

When **TuningS** is the selected Controller, select **OFF** for this setting.

- Use the **Protocol** setting to select the communication protocol.
 - Serial** — serial port connection through an Ethernet to serial server.
 - IP** — direct Ethernet connection.

When **TuningS** is the selected Controller, select **IP** for this setting.

- Use the **Tally** setting to turn camera tally **No** or **Yes**.
When **TuningS** is the selected Controller, select **No** for this setting.
- When **TuningS** is the selected Controller, use the **Stop On Shot** setting to select the camera to stop before recalling shots. Ross Video highly recommends selecting the **None** option to remove the delay between the controller and Caprica.
 - None** — do not stop any cameras. When this option is selected you must manually stop a camera before you recall a shot for the camera.

The **Stop On Shot** setting also has the following options:

- Single** — stop the camera used in the last shot recalled by Caprica. In some instances, the last used camera may not be the camera you want to stop.
 - All** — stop all the cameras. When running multiple cameras this option may stop a camera that you did not want to stop.
- Click **Apply Changes** to save the device settings.
 - Click **Done** to close the Configure REMOTE# panel. Click **Done** to close the Configure REMOTE# panel.

For More Information on...

- configuring remote devices for OverDrive systems that contain a Caprica Server, refer to the *Caprica User Guide*.

Device Setup

The control panel must be set up to communicate with the Caprica Server using the same serial or ethernet communications as you set up the Caprica Server to use.

- ★ The information in the following sections is provided as a guide and is based on the current version of hardware and software that was available at the time of testing. For the most accurate and up-to-date information, refer to the documentation that came with your device.

Control Panel Serial Communication

Set up serial communication for the various control panel models as follows:

- AW-RP400** — toggle Iris between Auto and Manu on the controller to toggle between Auto and Local on the switcher.
- AW-RP555** — set the REMOTE/SERVICE switch to R on the controller.
- AW-RP655** — set the REMOTE/SERVICE switch to N on the controller.

TECNOPOINT Srl Tuning Communication

Use the following procedure to set up communication with the TECNOPOINT Srl Tuning S controller:

- Launch the Tuning S software.
- Go to the **Group Server Setup**.
- Select the **Enable TCP/IP Server** option and enter the IP address and port to use.
- Select the **Enable Single Cell Replay** option and enter OK in the **Reply** box.
- Select the **Enable Global STOP** option and enter GLOBSTOP in the **Command** box.
- Select the **Enable Global START** option and enter GLOBSTART in the **Command** box.
- Select the **Enable Global CUT** option and enter GLOBCUT in the **Command** box.
- Select the **Enable Global Status reply** option and enter GET_STA in the **Command** box.
- Select the **Enable Global Group Select** option and enter SELECT## in the **Command** box.
- Select the **Enable Global Emergency Stop** option and enter EM_STOP in the **Command** box.
- Exit the **Group Server Setup**.

Best Practices

- Only configure one camera per driver when using the TECNOPOINT Srl Tuning S controller.
- When controlling several cameras, organize shots with each camera in a single column. For example: shots with camera 1 in column A, camera 2 in column B, and so on. Organizing camera shots in columns enables you to use only the row number to recall shots; the column comes from the camera number.

Compatibility

Robotic Camera	Version
Panasonic	-

Automation	Version
OverDrive	15.0 or higher
Caprica Server	1.0a or higher

Port Expanders	Support
Control DeviceMaster	Yes
Sealevel SeaLINK	Yes

Contacting Technical Support

Technical Support is staffed by a team of experienced specialists ready to assist you with any question or technical issue.

Ross Video has technical support specialists strategically located around the globe to ensure a prompt response to technical inquiries. Our primary technical support center is located in Ottawa, Ontario, Canada. In addition, we have offices in The United Kingdom (London), Australia (Sydney), and Singapore with satellite locations in New York City, The Netherlands, and China. As we expand our presence globally, we are constantly evaluating other key locations to have a local technical support specialist in order to better service our customers.

North America

Our North America center located in Ottawa, Ontario, Canada and is open Monday to Friday 8:30 a.m. to 6:00 p.m. EST, with 24/7/365 on-call service after hours.

Our telephone number is: +1-613-686-1557

Toll free within North America: +1 833-859-0499

EMEA

Our EMEA center is open Monday to Friday 8:30 a.m. to 5:00 p.m. GMT. After hours support is provided by our North America location.

Our telephone number is: +44 (0)1189502446

International toll free: +800 3540 3545

If the local support specialist is not available, your call will be transferred automatically to our North America center.

Australia

Our Sydney, Australia office is located in Alexandria, NSW.

Our local support telephone number is: 1300 007 677

If the local support specialist is not available, your call will be transferred automatically to our North America center.

Online

E-mail: techsupport@rossvideo.com

Website: open a support request using the link <https://support.rossvideo.com/> to open a support request.

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