



A NovAtel Precise Positioning Product

GrafNav / GrafNet
GrafNav Static

User Guide

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Foreword

Congratulations!

Congratulations on purchasing a Waypoint® Products Group's (Waypoint) software package. GrafNav / GrafNet® is a Windows®-based suite of programs that provide GNSS (Global Navigation Satellite System) data post-processing. Whether you have bought GrafNav / GrafNet or GrafNav Static, this manual will help you install and navigate your software.

Scope

This manual contains information on the installation and operation of Waypoint's GrafNav/GrafNet and GrafNav Static software packages to allow you to effectively navigate and post-process GNSS data. It is beyond the scope of this manual to provide details on service or repair, see *Customer Service* on page 10 for customer support.

How to use this manual

This manual is based on the menus in the interface of Waypoint's software. It is intended to be used in conjunction with the corresponding version of Waypoint's Inertial Explorer® software.

Prerequisites

To run Waypoint software packages, your personal computer must meet or exceed this minimum configuration:

Operating System

Windows XP®, Vista®, 7 or 8.

Processor

A Pentium or Xeon processor is required. Simultaneous forward/reverse processing is possible on dual CPU (Central Processing Unit) and Xeon systems. At least 256 MB of RAM is also required.

Although previous experience with Windows is not necessary to use Waypoint software packages, familiarity with certain actions that are customary in Windows will assist in using the program. This manual has been written with the expectation that you already have a basic familiarity with Windows.

Conventions

This manual covers the full performance capabilities of GrafNav / GrafNet GNSS data post-processing software. The conventions include the following:

-
- ☒ This is a note box that contains important information before you use a command or log, or to give additional information afterwards.
-

The term “master” refers to the reference station and the base station.

The term “remote” refers to a rover station.

This manual contains shaded boxes on the outside of the pages. These boxes contain procedures, screen shots and quick references.

Customer Service

If the software was purchased through a vendor, contact them for support. Otherwise, for software updates and customer service, contact Waypoint using the following methods:

Call: 1-800-NovAtel (1-800-668-2835) for North American access
1-403-295-4900 for International access

Email: support@novatel.com

Web: www.novatel.com/

1.1 Waypoint Products Group Software Overview

NovAtel's Waypoint Products Group offers GNSS post-processing software packages including GrafNav (a static/kinematic baseline processor) and GrafNet (a static baseline processor/network adjustment package). Both of these products have a Windows based Graphical User Interface (GUI) and use the same precise GNSS processing engine. This processing engine has undergone years of development effort and has been optimized to give the highest precision with the least amount of operator intervention.

This chapter contains a description of the hardware requirements, installation instructions and lists the CD contents. This chapter also provides an overview of the product packages (see *Table 1, Product Capabilities* on page 14).

1.2 Installation

The installation steps are in the shaded box.

1.2.1 What You Need To Start

Sentinel USB Key

This hardlock key is required to convert and process data. The hardlock key must be detected locally on the computer running the software.

Although USB key style licensing is the standard method, other licensing methods are available. Contact support@novatel.com for information about alternate licensing methods.

Installation file

You will receive an installation CD as part of your purchase. If you upgrade from a previous version, you will be provided with a link to Waypoint's FTP site where you can download the new setup file.

If you are restricted from connecting to FTP sites for security reasons, the 8.50 setup files are also available on a password protected website.

See *Prerequisites* on page 9 for the hardware requirements.

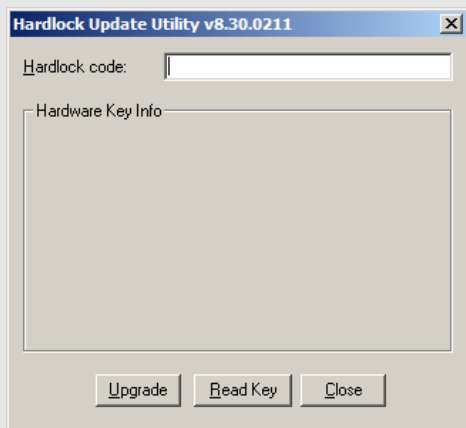


How to install Waypoint software

1. Download the setup files from Waypoint's 8.50 FTP site or password protected website. This is provided when a demo is requested or the software is purchased. Contact support@novatel.com with your four or five digit hardlock number for the FTP login information if required.

Alternatively, you may also have been provided with an installation CD.

2. Launch the setup and follow the on-screen instructions.
3. If you are upgrading from a previous version, you may need to upgrade your hardlock key. See *Section 1.2.3, Upgrading* on page 12 for more information.



How to upgrade your software

1. Install the software from either an installation CD or from the 8.50 FTP site.
If required, contact support@novatel.com with your hardlock key number for FTP login information.
2. Launch the hardlock upgrade utility through *Start | Programs | Waypoint GPS 8.50 | Utilities | Hardlock Upgrade Utility*.
3. Click the *Read Key* button to verify that the key is properly connected and that the Sentinel driver has been successfully installed.
4. Copy and paste the provided 16-character alpha-numeric key code and click the *Upgrade* button.

1.2.2 CD Contents and Installation

GrafNav / GrafNet is distributed on a CD. The latest version is also kept on our 8.50 FTP site and a password protected web page. Contact support@novatel.com to obtain login information if required.

There are a number of folders on the CD and the FTP site that contain additional programs and data. These include the following:

Data

This directory contains sample GNSS data for GrafNav and GrafNet. Browse through the subdirectories to see what data is available. To process, copy the contents of directories to the hard disk.

Geoid

This directory contains geoid files for the U.S. (Geoid03, Geoid09, Geoid12 and Geoid12A), Mexico97, Australia (AusGeoid93 and AusGeoid98) and the world (EGM96, EGM2008). It also contains geoid files for other regions. These files allow mean-sea-level (orthometric) heights to be computed using GrafNav and GrafNet. Files are in the WPG (Waypoint Geoid) format. Contact support@novatel.com for more information about geoid availability for other regions.

Doc

Contains this manual in Adobe Acrobat PDF format.

1.2.3 Upgrading

Waypoint's software is distributed with a Sentinel USB key. Upgrading to a major new version (for example, 8.40 to 8.50) requires a hardlock upgrade code. This code is used in conjunction with the hardlock upgrade utility.

1.3 Processing Modes and Solutions

The types of solutions are described in the shaded box. The following are the types of processing modes:

Static

Static processing involves the determination of a single coordinate for each static session detected. There are two types of static solutions supported by GrafNav: float and fixed solutions. They are discussed in the shaded box.

Kinematic

When processing kinematic data, it is generally of interest to optimize the entire trajectory. This is in contrast to static processing, which solves one coordinate for the entire session.

In order to quickly achieve cm-level accuracy in kinematic processing environments, ARTK is used to resolve carrier phase ambiguities. This is discussed in the shaded box.

Processing Solutions

Fixed static solution

In a fixed static solution, data from an entire static session is used in a least-squares type solution to resolve the carrier phase integer ambiguities. Fixed static solutions are associated with high levels of accuracy (mm to cm level).

Fixed static solutions are attempted by default within GrafNet if the baseline length is 40 km or less. Fixed static solutions can also be processed in GrafNav, although it is not the default method of processing (see *Fixed Static* on page 54 for more information).

An appreciable change in satellite geometry is required for a fixed static solution to be successful. Thus, the minimum recommended session lengths are 15 to 20 minutes for short to medium baseline lengths under open skies.

Fixed solutions are most reliable on baselines less than 30 km for dual frequency and 5 km for single frequency, although they can still succeed on longer baseline lengths.

ARTK solution

ARTK solutions, like fixed static solutions, are associated with high position accuracy. However unlike a fixed static solution which requires appreciable changes in satellite geometry over the session, ARTK is optimized for kinematic applications and attempts to resolve carrier phase ambiguities as quickly as possible.

With short baseline lengths (several kilometers), open sky conditions and dual frequency data, ARTK often achieves cm or cm-level accuracy using only several seconds of data. ARTK requires a minimum of five satellites. Although it may resolve at baseline lengths as long as 70 km, it is most reliable at distances of 30 km and less provided dual frequency data.

Float solution

Float solutions, unlike fixed static and ARTK solutions, do not resolve carrier phase ambiguities as integers. As such, they are associated with lower accuracy applications than fixed solutions. Provided good data, float solutions improve with time and can still achieve sub decimeter accuracy, depending on other factors such as baseline length, number of satellites and geometry, raw measurement data quality, etc.

Table 1: Product Capabilities

Capabilities	GrafNav Static	GrafNav/GrafNet
Float Static	✓	✓
Float Kinematic		✓
Fixed Integer Static (Fixed Solution)	✓	✓
Fixed Integer Kinematic		✓
Dual Frequency	✓	✓
Multi-Base Processing		✓
PPP	✓ (Static only)	✓
Moving Baseline		✓
Azimuth Determination		✓
IMU Processing ^a		

a. Refer to the *Inertial Explorer User Manual* available on our website at www.novatel.com.

Moving Baseline Features within GrafNav

Relative Processing

All of the same advanced GrafNav processing features including ARTK, a robust Kalman filter, and forward/reverse processing are also supported in moving base processing. The only restriction is that only one base station can be used when processing the relative vector.

For applications where both antennas are mounted on the same vehicle, the surveyed distance between the antennas can be entered to assist ambiguity resolution. Heading can also be computed for these applications.

Relative Vector Output

After processing, the included Export Wizard profiles are available to output the relative vector in local level or ECEF format.

Relative Velocity

In addition to relative position information, GrafNav uses Doppler measurements to compute instantaneous relative velocity between two moving antennas.

1.4 Overview of the Products

1.4.1 GrafNav

GrafNav is a kinematic and static GNSS post-processing package. Included with GrafNav is a Precise Point Positioning (PPP) module, support for multi-base applications, and support for moving base applications. See *Chapter 2, GrafNav* on page 17 for more information.

1.4.2 GrafNet

GrafNet is a batch static baseline processor and network adjustment package. It is often used to check or establish base station coordinates for later use within GrafNav or to survey static networks. See *Chapter 3, GrafNet* on page 101 for more information.

1.4.3 GrafNav Static

GrafNav Static includes GrafNav and GrafNet, however only static data can be processed. See *Chapter 2, GrafNav* on page 17 for more information.

1.4.4 Moving Baseline Features

GrafNav features a moving baseline module that processes GNSS data between two moving antennas. Heading can also be computed if the two antennas are mounted on the same vehicle.

1.4.5 Inertial Explorer

Inertial Explorer shares a similar interface with GrafNav and provides both GNSS and INS processing capabilities. Inertial Explorer is powerful and feature rich, including support for both loosely and tightly coupled processing, multi-pass processing, a backsmoother, automatic processing environment detection and many other features.

See www.novatel.com/products/software/waypoint-products/post-processing-software/inertial-explorer/ for more information.

1.5 Utilities

The following utilities are installed automatically with GrafNav and can be accessed from *Start | Programs | Waypoint GPS 8.50 | Utilities*.

1.5.1 Copy User Files

This utility is intended for those upgrading from a previous version (such as 8.40). It copies any user created content from a previous version to the new version. Examples of user created content include custom datum and grid definitions, Export Wizard profiles and user defined favourites.

☒ It is for this reason we do not recommend uninstalling previous versions prior to installing version 8.50.

1.5.2 Download Service Data

This utility allows you to search for freely accessible base station data provided by government organizations. The utility fully supports both GPS and GLONASS and will download, convert, and if necessary resample and concatenate the downloaded data so that it is ready to be used within your project.

The download utility can also be used to obtain precise satellite clock and ephemeris data, GPS and GLONASS almanacs and alternate broadcast ephemeris files.

1.5.3 GPB Viewer

This utility allows you to view converted GNSS data as well as perform certain functions, such as changing the static/kinematic processing flag. See *Chapter 5, Utilities* on page 141 for more information.

1.5.4 Mission Planner

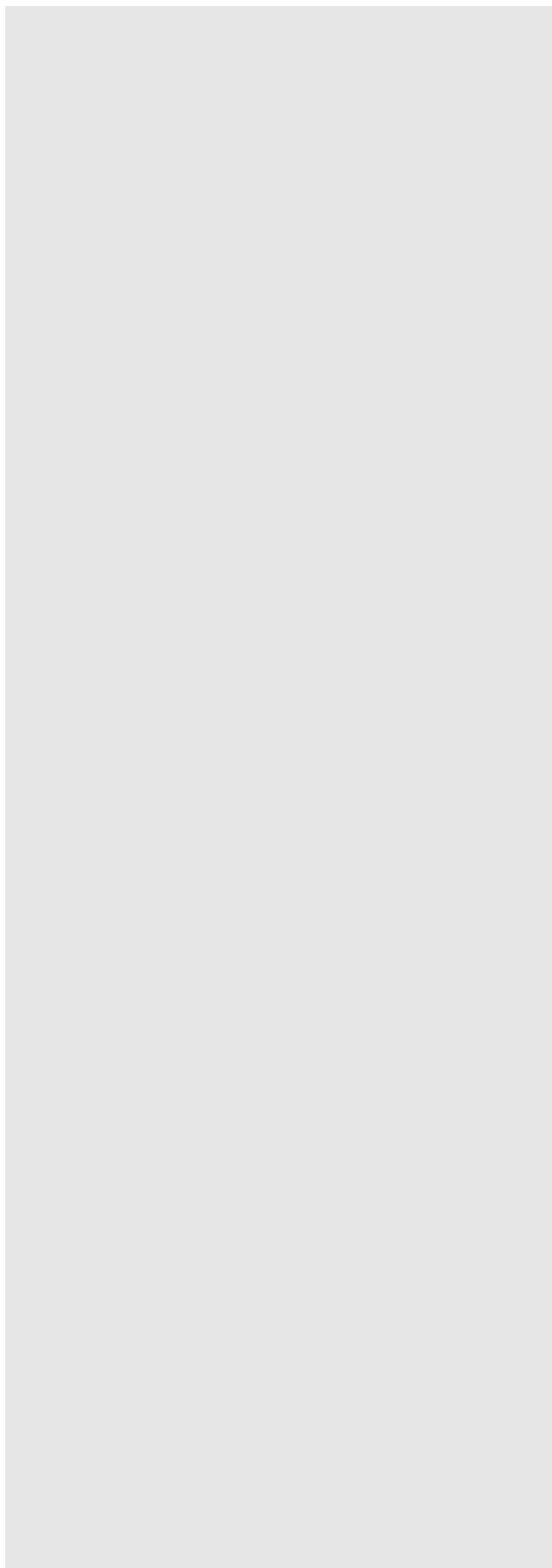
This utility is found under the *Tools* menu and supports both GPS and GLONASS constellations. It is used to predict satellite count and DOP values ahead of time.

1.5.5 Data Converter

This utility converts raw GNSS data files into Waypoint's own format. See *Table 2, Supported Data Formats for Post-Processing* for supported receivers and formats.

Table 2: Supported Data Formats for Post-Processing

Make	Model
NovAtel	All Models
Javad	All Models
Leica	System 500 System 1200 GX1230
NavCom	SF-20x0 SF-30x0 Sapphire
RTCM	3.0
Septentrio	SBF
Ashtech	Real Time B-file DSNP
Trimble	4000 series (DAT) 4000 series (RT) 5700
U-Blox	Antaris
RINEX	2.0 2.1 2.11 3.0



2.1 GrafNav and GrafNav Static Overview

GrafNav

GrafNav is a full-featured kinematic and static GNSS post-processing package that uses a proprietary GPS and GLONASS processing engine. It supports single and multi-baseline (MB) processing, moving baseline processing, Precise Point Positioning, and directly supports many different receiver formats. For any receiver formats not currently supported, RINEX files can be imported. See *Table 2, Supported Data Formats for Post-Processing* on page 15 for more information.

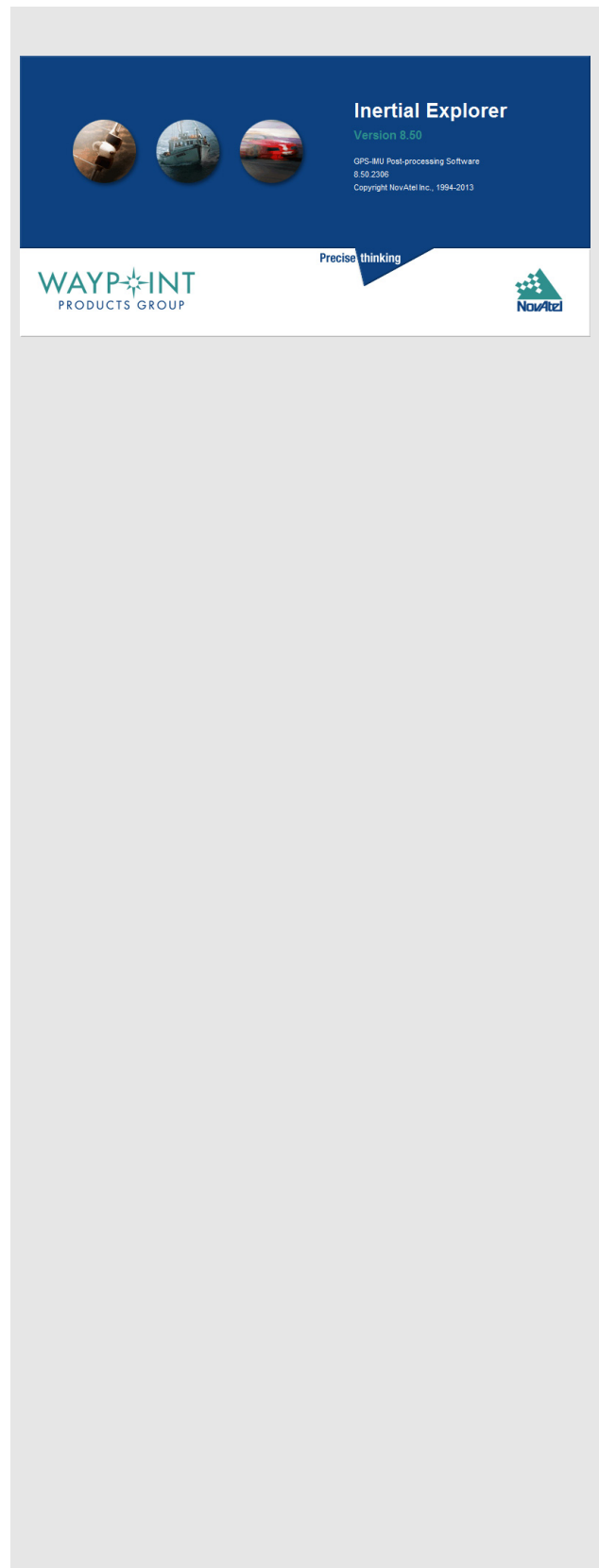
This chapter describes how to get started with GrafNav and goes through each menu of its interface. Step-by-step instructions for first-time users are also included.

GrafNav Static

This chapter also describes the features of GrafNav Static.

GrafNav Static provides the same processing features as GrafNav, but only for static baselines.

See *Table 1, Product Capabilities* on page 14 for a capability comparison between GrafNav and GrafNav Static.



2.2 Start a Project with GrafNav

New users will find it easiest to create a new project with the New Project Wizard. The Wizard takes you through all the steps of creating a GrafNav project, including data conversion and downloading base station data (if needed). The only requirement for using the Wizard is that you have a raw GNSS data file downloaded to your computer. Access the Wizard through *File | New Project | Project Wizard*.

After you have become familiar with the GrafNav interface, you may prefer to create new projects using one of the other two supported methods. That is, creating an *Empty Project* or using *Auto Start*. Both of these methods involve using some of the utilities included with GrafNav prior to starting the project. Specifically, if creating a new project outside of the New Project Wizard, you need to first convert your data using the Raw GNSS conversion utility and download any base station data using the Download Service Utility. See *Section 5.4, GNSS Data Converter Overview* on page 147 for a description of the Convert Utility, and *Section 2.8.12, Download Service Data* on page 94 for instructions on the Download Utility.

Before you start a project in GrafNav, you need to verify installation, convert data and download any required data.

Install Software

Verify that the installation was successful by ensuring that you have a *Waypoint* program group on your computer. If this program group is not there, see *Chapter 1, Introduction and Installation* on page 11 for installation instructions.

Convert Data

Raw GNSS data files must be converted into Waypoint's GPB format. See *Section 5.4, GNSS Data Converter Overview* on page 147 for a complete description of the *Convert* utility.

The *GPBView* utility can be used to switch between static and kinematic mode.

Download Service Data

If no data was logged from a reference station, you have the option of downloading free GNSS data from the Internet.

A reference station can also be added directly from a list. See *Section 2.8.12, Download Service Data* on page 94 for these instructions as well as a complete description of the *Download* utility.

2.3 File Menu

2.3.1 New Project

To process a survey for the first time, start a new project. When you start a new project, choose between *Project Wizard*, *Auto Start* and *Empty Project*.

The Project Wizard is recommended for new users as it will guide you through all the steps of getting started, including data conversion and downloading base station data (if needed). After you are more familiar with GrafNav's tools and workflow, you may prefer to use either the *Empty Project* or *Auto-Start* option.

This section discusses these options and gives step-by-step instructions once you have decided on the method for starting your project.

Project Wizard

The Project Wizard offers you a guided step-by-step way of creating a project. The *Project Wizard* steps are listed in the shaded box

Auto Start

Auto Start prompts you for all the information required to process a data set. This option allows you to add master and remote stations and to use a project setting that best suits your application. The *Auto Start* steps are in the shaded box.

-
- ☒ Files should be converted to GPB format before using Auto Start. For more information about converting your file, see *Section 5.4, GNSS Data Converter Overview* on page 147.
-

Project Wizard Steps

1. Create and name the project.
2. Add rover data to the project.

-
- ☒ The rover data can be in Waypoint's GPB format, or in the receiver's raw format, in which case the Wizard converts it to GPB for you.
-

3. Add base station data to the project.

-
- ☒ You can add your own local base station data (in raw or GPB format) or you can have the Wizard download free service data from the Internet.

If you plan to process with PPP, you can skip adding base station data and download the precise satellite clock and orbit files from the Internet

How to create a new project using Auto Start

1. Select *File | Auto Start | Browse* to name the new project. Use the *Add* button to choose master station file(s).
2. Use the *Browse* button to choose the remote file. The master and remote station files must contain data collected during the same time period. To see the time that the data was collected, click the *Plot Coverage* button to display the *File Data Coverage* plot.
3. In *Settings*, choose the processing profile that best suits your application.
4. Enter the master station coordinates and antenna information.
5. Enter the remote station antenna information.

-
- ☒ See *Section 2.5, Process Menu* on page 42 for more information on processing.
-

How to create a new project using *Empty Project*

1. Select *File | New Project | Empty Project*.
2. Enter the name and where you would like to save your project.
3. Select *File | Add Master File(s)* to load master files. Select the GPB files collected at the base station(s) and click *Open*.
4. Enter the base station coordinates, datum and antenna information when prompted.
5. Select *File | Add Remote File*. Select the GPB file corresponding to the data that was collected at the remote.
6. Enter the antenna information for the remote when prompted.
7. Select *Process | Process GNSS*.
8. Ensure an appropriate processing profile is selected prior to processing.

How to open a project

1. Choose *File | Open Project*. A dialog box appears that asks you to select the name of an existing project (CFG file).
2. Choose the name of the project and click the *OK* button.

How to save a project

1. Choose *File | Save Project*.

How to save a project “as”

1. Choose *File | Save As*.
2. Enter the name, file format and where you would like to save your project.

☒ Entering the name of a project that already exists overwrites the file contents.

How to print

1. Select *File | Print*. A dialog box appears.
2. Choose the printer.
3. Choose the item you would like to print.
4. Set the page orientation, color and any other settings you need.
5. Click the *OK* button.

Empty Project

Creating an empty project is not recommended for new users as all steps involved with project creation must be done manually. Specifically, the remote GNSS data must be converted to GPB format using the GNSS Data Converter utility and any base station service must be downloaded through the Download Service Data Utility.

The Project Wizard is best for new users as it guides you through each step involved with starting a project. Creating an empty project is usually preferred by advanced users. This is because, for someone familiar with GrafNav's workflow, it may be possible to get started more quickly creating an empty project as opposed to going through each step of the Wizard. The steps involved with creating an empty project are in the shaded box.

2.3.2 Open Project

This option allows you to open existing projects.

2.3.3 Save Project

GrafNav automatically saves the project before processing.

2.3.4 Save As

Use the *Save As* command under the *File* menu to create a new project that has identical processing options as the current project. This allows you to change the options in the new project and process the data without losing the solution computed by the original configuration.

2.3.5 Print

This option allows you to print various items including windows, plots and text files.

2.3.6 Add Master File(s)

Steps for how to add a master station are in the shaded box.

Master Station Position

When loading a master station, the coordinates that appear in the master coordinate dialog may come from two different sources.

If loading data converted from RINEX, as is the case when obtaining base station data through the Download Service Data Utility, the coordinates that appear initially are scanned from the RINEX header. The coordinates provided in the RINEX header may be precise or approximate, this will depend on the individual RINEX data provider.

If loading base station data converted from any other source, the coordinates that appear initially are likely averaged from the unprocessed position records decoded in the raw GNSS data file. The accuracy of this position is typically no better than approximately 2 m horizontally and 5 m vertically. If you select the *OK* button using averaged coordinates, a warning dialog appears to ensure you are aware the coordinates may not be accurate enough for your application.

Regardless of the source of your base station data, it is important that accurate coordinates are loaded. In differential processing, a vector is solved between the base station antenna and the remote antenna. Any error in the base station position is directly transmitted to the remote position.

To assist in loading precise coordinates, it is recommended that coordinates be selected from the favourites list through the *Select from Favourites* option. Coordinates for select base station networks, such as CORS and IGN, are regularly maintained and accessible through Favourites.

The *Compute from PPP* option can be used to easily check or survey base station data using GrafNav's Precise Point Processor. When using this option, the difference between the loaded and computed coordinates is displayed. Note that PPP accuracy is largely dependent on the length of the survey.

Datum Selection

In differential processing, a vector is solved between the base station and the remote. Your project datum is thus not controlled by what you select as your processing datum, but rather the actual base station coordinates entered.

Regardless, it is important to ensure you have correctly set the processing datum after entering the base station coordinates. This is partly because the processing datum is documented in the header of all export files generated by

How to add a master file

1. Select *File | Add Master File(s)*.
2. Select the base station file(s) from the list of available GPB files. Up to eight base stations can be added to a GrafNav project. Click the *Open* button.
3. Enter the coordinates of each base station when prompted.
4. Verify that the coordinates match your selected processing datum.
5. Enter the antenna model and height information and click the *OK* button.

the Export Wizard. If it is incorrectly set, your results could be interpreted by another person as being in the incorrect datum.

Antenna Height

The antenna height entered in this box applies primarily to kinematic trajectories and static sessions. If exporting camera marks/features, you are provided the opportunity to apply an offset during export. As such, if you are interested primarily in exporting camera events, we recommend entering an antenna height of zero as measured to the Antenna Reference Point (ARP).

Antenna Models

The purpose of an antenna model is to:

- Correct for the vertical offset between where GNSS observations are observed (the electronic phase center) and the bottom of the antenna (Antenna Reference Point, or ARP).
- Correct for any difference between the L1 and L2 electronic phase centers, which can be a factor in the success or failure of ambiguity resolution.
- Apply small elevation based corrections (mm level)

GrafNav 8.50 supports absolute antenna models as provided by the NGS. If the antenna model is not known at your remote, it is recommended that the *Generic* profile be applied, which does not apply any corrections. In that case, the processed position is referenced to the antenna L1 phase center. However, the correct antenna model should be selected for best results.

When selecting an antenna model, the *Applied height* reflects the vertical offset between the L1 phase center and the ARP (which is the bottom of the antenna). This value comes directly from the antenna model and reduces the processed position from the phase center to the bottom of the antenna. This value should match any diagram that appears directly on your antenna, presuming it is an absolute antenna calibration. Antenna heights can be measured to the antenna reference point, phase center, or computed from a slant measurement.

When loading a base station converted from RINEX, the antenna name and radome (if provided) are scanned from the RINEX header and used to automatically load the appropriate antenna profile. It is good practice to ensure the correct antenna model is loaded prior to processing.

2.3.7 Add Remote File

The remote file contains the raw GNSS measurements that are processed together with data from known base station(s). The remote file must be converted to GPB format prior to loading. When adding a remote GPB file, you are prompted to enter the antenna information. See *Antenna Models* on page 22 for more information.

2.3.8 Add Precise Files

Broadcast Ephemeris

The broadcast ephemeris data is necessary for GNSS data processing.

The ephemeris file contains Keplerian orbital parameters used to compute satellite positions. Presently, the line of sight component of satellite positions can be computed within an accuracy of approximately 2 m (RMS) using the broadcast ephemeris.

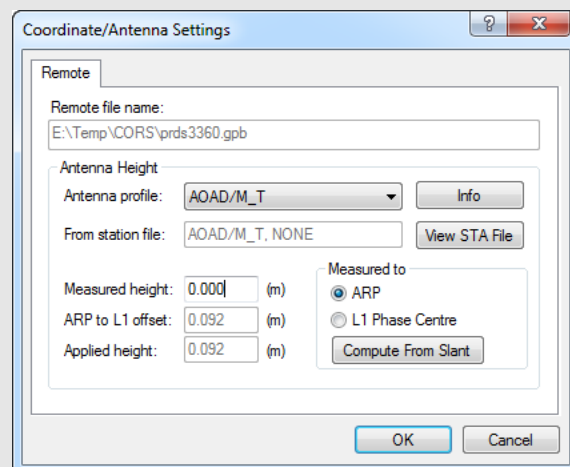
Orbital error is largely removed in differential processing, as the line of sight component of orbital error is heavily correlated at short and medium baseline lengths. Therefore, the accuracy of the broadcast orbits is completely sufficient for most projects. A discussion on precise orbits is found in the next section.

Generally, the GNSS receiver includes broadcast ephemeris data with its raw data files. The decoder converts these files into EPP format. Receivers typically output ephemerides at startup, as satellites rise into view, or approximately every two hours.

Prior to processing, GrafNav combines all ephemeris information collected at the base station(s) and remote. This minimizes the chance of missing ephemerides, which will cause affected satellites to be rejected from processing.

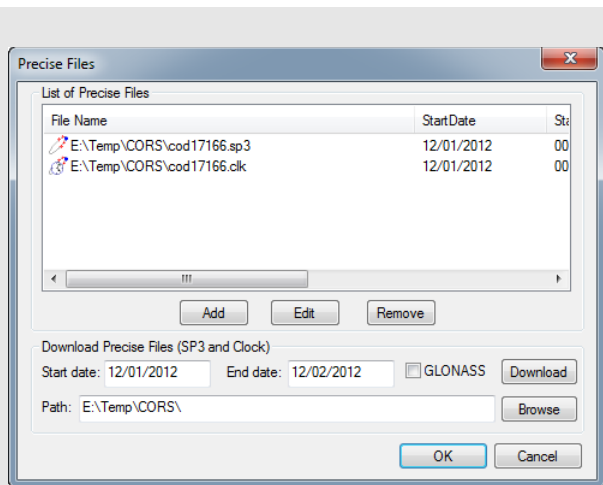
If no broadcast ephemeris information was recorded, or if it is known that some ephemeris data is missing, the Download Service Data utility can be used to download global broadcast orbits in EPP format. This option is available from the *Other Files to Download* section of the *Options* tab of the download utility.

It is a common misunderstanding that missing broadcast orbits can be overcome by downloading precise orbits. This is untrue, as precise orbits provide only corrections to the broadcast orbits. Therefore, a full set of broadcast orbits are still required, regardless of whether or not precise orbits will be applied in post-processing.



How to add a remote file

1. Select *File | Add Remote File*.
From the list of available GPB files, choose the file collected at the remote station.
2. When prompted, enter the remote station antenna information.



How to download precise ephemeris files

1. Select *File | Add Precise Files*.

The project start and end date are automatically scanned from the GNSS data loaded into the project. This should not need to be set manually.

2. Select *Browse* in order to choose any precise orbits (.sp3) that have previously been downloaded.

If no files have been downloaded, select *Download* and the precise orbit (.sp3) and clock (.clk) data will automatically be downloaded and added to your project. This requires an internet connection.

- ✉ If your project includes GLONASS data, you may wish to select the *GLONASS* option prior to downloading. This will direct the download utility to retrieve products that include GLONASS corrections in addition to GPS. The default search location for precise products contains only GPS data.

Precise Ephemerides

Precise ephemerides contain corrections to broadcast orbits. These files are produced by various agencies, including CODE (Center for Orbit Determination), the IGS, and many others. The different precise ephemeris products vary in their latency, with presently supported products ranging from approximately 6 hours to 2 weeks. The difference in accuracy between rapid and final products is very small, generally within the noise of either differential or PPP solutions.

Presently, precise ephemerides reduce the line of sight component of satellite position error to approximately 2 cm RMS (as compared with approximately 2 m RMS for broadcast orbits). As orbital error is largely cancelled in differential processing, adding precise ephemerides to a differential project will only produce observable differences where the baseline length is very large (150-200 km). For this reason, adding precise orbits to a differential project is generally considered optional. However, it is required for PPP projects.

Precise ephemerides can be downloaded through the Download Service Data utility or directly through the GrafNav interface. The latter method is described in the shaded box.

IONEX Files

IONEX (Ionosphere Map Exchange) files contain a model of the TEC (Total Electron Content) of the ionosphere. These files can be applied to assist long distance L1 only processing. As such, these corrections are not of interest to the majority of GrafNav users. These files are ignored if dual frequency ionospheric processing is engaged.

Satellite Clock Files

Presently, using the data available in the broadcast ephemeris, satellite clock errors can be predicted within an accuracy of approximately 2 m RMS. Satellite clock error is completely removed in differential processing, as this error is exactly the same at the base and the rover. Thus adding precise clock files to a differential project will have no effect. Precise clock files are required for PPP processing, as otherwise meter level errors would result.

Satellite clock files can be downloaded through the Download Service Utility or from *File | Precise Files*.

2.3.9 Load

GNSS Solution

After processing, forward and reverse solutions are automatically combined if available. Thus the trajectory output to the map window, and all generated plots, are usually relative to a combined forward/reverse solution. The title bar of the map window and plots clearly indicate which solution is loaded.

If the processing results from a particular direction (forward or reverse) are of interest, individual solutions can be loaded using this feature.

PPP Solution

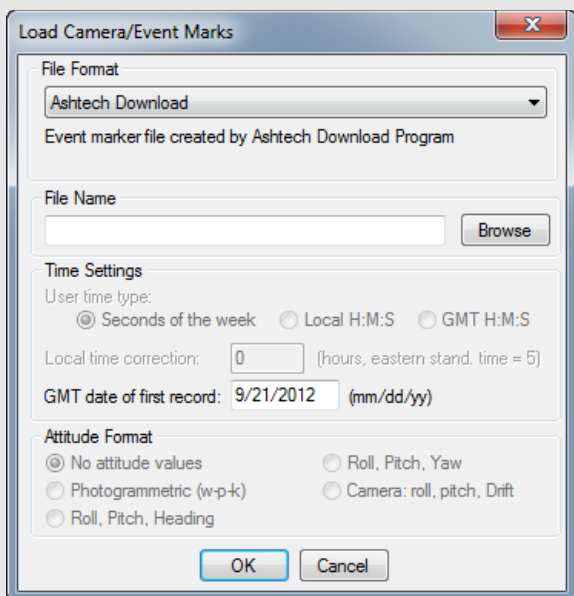
GrafNav's differential and PPP trajectory files have, by design, different file extensions. This allows both differential and PPP trajectories to be processed within the same project without overwriting each other. If both types of solutions have been processed, you can control which type of solution is loaded through the *GNSS Solution* and *PPP Solution* options.

Any Solution

This option allows any GrafNav readable trajectory to be loaded into a project. The only requirement is that the trajectory cover the same time range as the data within your existing project. An example of when this feature may be used is when loading a real time trajectory produced from the GNSS decoder.

Single Point Solution (from .gpb file)

This option ensures the trajectory displayed to the map window reflects the unprocessed positions in the remote GNSS data. This trajectory typically represents the real time solution as computed on board the receiver during data collection.



How to load camera event marks

1. Under *File*, select *Load | Camera Event Marks*.
2. Choose the file format that matches your input file.
3. Under *File Name*, use the *Browse* button to select the file of interest. The file name depends on the receiver format and is explained in *Section 2.3.6, Add Master File(s)* on page 21.

- ✉ If the files formats you use are User1- User6, use *Time Settings* to select the time formats. UTC time cannot be loaded and the correction has to be applied externally.

Loading Camera Event Marks

Use this feature to load external time-tagged events from an ASCII file. When you load these events, they must be referenced to GPS time and not UTC (coordinated universal) time. The source of the events can come from an aerial camera, sounding equipment or other real-time devices. The GPS receiver must support a mark or pulse input for this feature to work.

Most events are automatically stored in the station file (.sta) during the conversion to GPB format and appear when the remote is added to the project. For user events, and a few receivers such as Ashtech or B-file, this feature must be used.

File Format

STA File

Many new converters save the camera event marks directly to the station file. The marks load when you add the GPB file to the project. If they do not load, then use the *File | Load | Station File* feature.

MRK File

Leica SR receivers save event marks into a EVT file, which is converted into a MRK file by the Leica decoder. The MRK file can be loaded using this option. Numbering is performed by the converters.

Ashtech Download

Ashtech receivers with internal memory usually output a PHOTO.DAT file after the receiver data has been downloaded using HOSE or another corresponding utility. Newer variants might be under the format M???.###. Either file can be loaded using this option. The GMT date of the first event mark must be entered if it is not detected. Events are automatically numbered starting at 1.

Leica GeoSystems

EV0 and TDU files are produced by the Leica software and can be imported using this option. This file might contain time in the local time zone. If not, enter the time zone offset as zero. The time zone correction and the GMT date of the first mark must be entered. Events are automatically numbered starting at 1.

LH-Systems Ascot

LH Systems ASCOT (RC-30) has a format very similar to EV0 except that it contains the relative angles of the camera mount, which can be used to apply a 3-D offset for the antenna/camera difference.

User#

These formats allow you to import the time and name of each event mark. Optional variables include line number (description) and altitude information.

File Name

The file name depends on the receiver format. Examples include the following:

- NovAtel is MRK
- Ashtech is PHOTO.DAT
- Trimble is SUM
- Leica is EVO

Time settings***User time type:***

Seconds of the week – GPS time ranging from 0 to 604800.

Local H:M:S – Local hours, minutes and seconds (HH:MM:SS.SSSS).

GMT H:M:S – GMT hours, minutes and seconds (HH:MM:SS.SSSS).

Local time correction:

This is necessary for both Leica and User# formats using *Local H:M:S*. This is the offset, in hours, from GMT. For the Eastern Standard Time zone, this number is 5. For the Pacific Standard Time zone, this number is 8. During daylight savings time, these numbers are reduced by one. An incorrect entry causes the camera marks to be displayed incorrectly or not be displayed at all.

GMT date of first record:

This is necessary for Leica, Ashtech and User# formats implementing H:M:S time-tagging. Enter the date of the first exposure record in month/day/year format. It is not the date in local time, which may differ towards the end of the day. An invalid date results in the marks not being displayed.

Attitude Format

For *User5* and *User6* formats that include attitude information, a definition of how the angles are defined is required. Currently, the following attitude formats are supported:

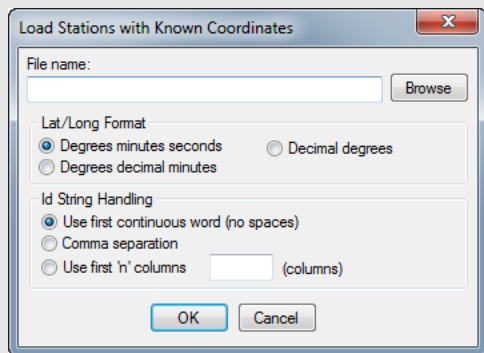
Photogrammetric (w-p-k):

These angles are defined as omega primary, phi secondary and kappa tertiary (ground-to-air).

Camera (roll, pitch, drift):

These angles are the relative ones between the frame of the camera and that of the aircraft.

If the raw GPS receiver data logs position records, there are small circular event marks on the trajectory map in bright blue. These also appear if the data has been processed. If no event marks are present after processing, then it is likely that the time tags are



How to load Stations with known latitude and longitude

1. Select *File | Load | Stations with Known Lat/Long*.
2. Choose the file, under *File Name*, that contains the station information in one of the formats from the *Lat/Long Format* option list.
3. Choose the format, under the *Lat/Long Format*, that the coordinates from the file are in.
4. Choose an option under *Id String Handling* to tell the program how to separate the ID from the coordinates. The first column usually contains the station IDs.

wrong or no event marks have been loaded. To determine what has been loaded, use the *Feature Editor* by selecting *View | Features*.

Station File (.sta/nst)

GrafNav automatically loads the station file (.sta) associated with the remote GPB file. This file is produced during conversion and contains, among other information, any camera events. If properly loaded, these camera events are displayed to the map window.

The program automatically loads the STA station file as long as the filename is the same as that of the remote GPB file. If the station file has a different filename than the GPB file, then load the file separately. Most decoders produce station files.

RTK Dat File (.sta/nst)

This option loads converted RTK solution files and then uses the Export Wizard to re-format them for output.

Stations with Known Lat/Long

This option allows you to load and display a file that contains stations with known coordinates. The coordinates are displayed with pink triangles.

Lat/Long Format

This is a list of formats that the coordinates from the file are in. These formats include the following:

Degrees Minutes Seconds

For example: 51° 03' 28.3214"

Degrees Decimal Minutes

For Example: 51° 03.4720'

Decimal Degrees

For Example: 51.0579°

Id String Handling

The settings under this option tell the program how to separate the ID from the coordinates.

Use first continuous word (no spaces)

To be used if the station names are separated from their coordinates by a space.

Comma separation

Use this option if commas separate the IDs from the coordinates.

Use first 'n' columns

If you know which column the coordinates start in, you can enter the number for the program to begin at. Each character is a column.

Leica IDEX File (.idx)

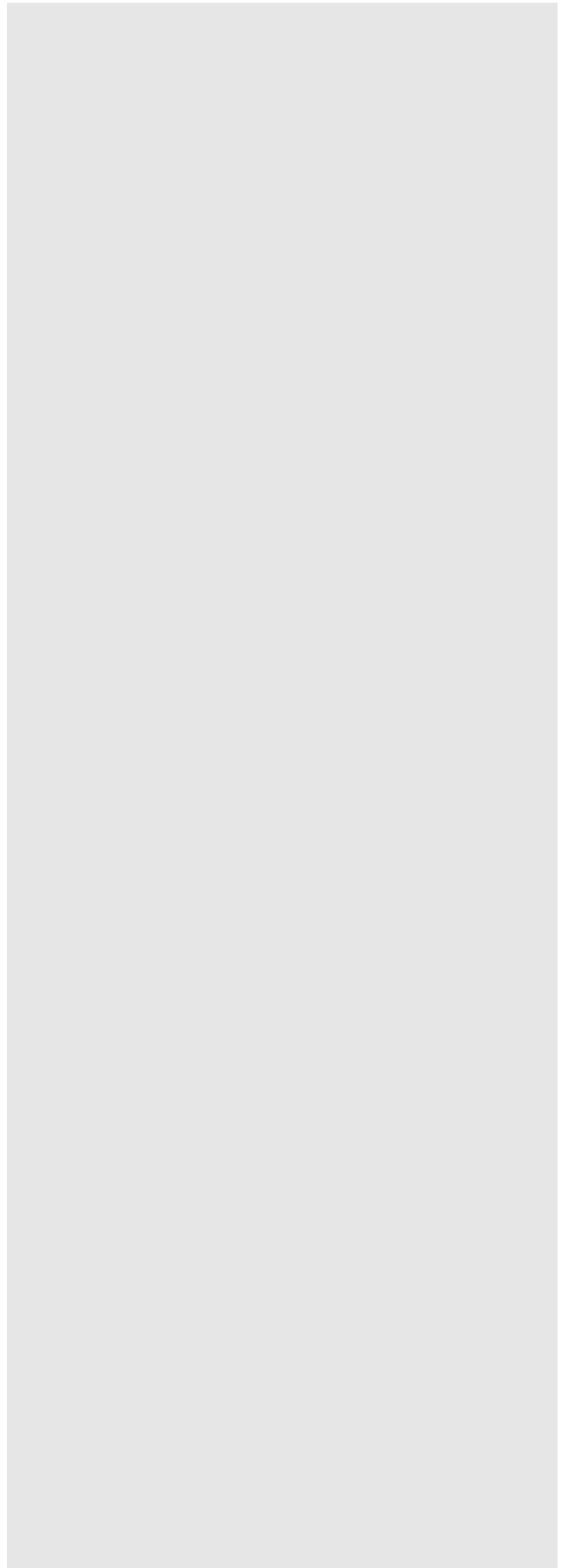
Time-tagged points created with Leica 5 data collectors can be given a name, position and antenna height. However, firmware versions 3.0 and greater do not store the station names within the TTP file. These names are stored within the database structure (control.db) and cannot be accessed directly by the software. The point information contained within the database has to be converted to ASCII, which is done by creating an IDEX file using Leica's Ski software.

Once an IDEX file has been created, it can be loaded into GrafNav. You should see a message indicating how many IDEX points were matched to TTP points. After processing at least one direction, the TTP points should be visible and numbered sequentially. These have been loaded from the STA file.

Points are matched via their times. Often, there are fewer matched points than the original number of TTP points due to several reasons, including the deletion of points in the field, and/or the addition of static session marks.

Ashtech OUT File (.out)

This type of file is created by Ashtech's Seismark surveying system and can be loaded into a project.



How to import a Digital Elevation Model (DEM)

1. Select *File | Load | Digital Elevation Model | Import DEM Points*.
2. Browse to the DEM points (.pts) file in *File*.
3. Select a format under the *Format Menu* to organize the DEM file.
4. Select the options that you would like to use to help read the input file.
5. Click *Import*. It takes the program some time to form a TIN model.
6. Click *Accept* after the geoid is formed and a TRI file is saved.

☒ If no contour lines are visible, the DEM may be outside of the project area.

How to load a DEM

1. After a DEM has been imported, select *File | Load | Digital Elevation Model | Load Triangulation (*.tri)*.
2. Select the formed TIN file and click *Open*.

DEM file format options:

First field contains ID string

Shows if a point name leads each line.

Stop reading if incomplete line encountered

Aborts if there is any line missing from the required fields.

Skip 'n' lines at start

Skips past any header lines in the file.

Reject DEM points outside GPS observation area

This option is recommended because it limits the size of the DEM to just the GPS observation area. To use this option, valid GPS position data has to be available from the GPS receiver or through processing.

Reduce DEM density using error tolerance

Rejects points if their height can be estimated from nearby ones within the error tolerances that are defined. Tolerances of 5-10 m are acceptable for VSF purposes. Larger error tolerances reduces densities significantly. This option should be used if you have either a DEM grid or a large high-density DEM that causes memory or speed problems.

Digital Elevation Mode (DEM)

You may import a DEM after loading the remote GPB file. Loading a DEM into a GrafNav project provides access to the *Height Above Ground* plot after processing. It is also applied when exporting VSF ellipsoidal or orthometric heights, however this is no longer required by most photogrammetric packages.

DEM Points File

File

The DEM file has to be organized in one of the formats listed under the *Format* drop-down list.

Format

These options are available to help read the input file. They are listed in the shaded box.

Grid

This option defines the DEM source or working grid. If the horizontal coordinates of the DEM are in a map projection, such as UTM (Universal Transverse Mercator) or State Plane, then GrafNav requires the details associated with this projection. If the DEM is stored in geographic coordinates, then a working map projection (grid system) is required. UTM is the easiest, but any system will do.

Datum

This option specifies the processing datum for the project, which should match the datum that the DEM values are stored in. Since only the ellipsoid component of the datum is used, NAD83 and WGS84 can be used in place of each other for most applications that do not require the utmost DEM accuracy.

Geoid

A geoid model should be selected since DEMs are generally referenced to MSL (Mean Sea Level). Waypoint geoids are in WPG file format and many of them are accessible directly from the NovAtel website. Contact support@novatel.com if you need help finding geoid files that can be used within GrafNav.

☒ After a DEM has been imported, the TIN model does not need to be re-formed. Load the TRI file by selecting *File | Load | Digital Elevation Model | Load Triangulation (*.tri)*.

2.3.10 Convert

The two conversion utilities that are available are the following:

Raw GNSS to GPB

You must convert your raw GNSS data files to GPB format prior to importing them in to a GrafNav project. See *Section 5.4, GNSS Data Converter Overview* on page 147 for more information regarding this utility.

GPB to RINEX

GNSS manufacturers typically provide a utility to convert their native data format to RINEX. It is therefore unusual to convert from GPB to RINEX, as an intermediate step would be involved (converting to GPB) when often the native receiver data can be converted directly to RINEX.

Nonetheless, RINEX 2.11 and 2.0 files can be generated from GPB files using this utility. See the shaded box for more information.

2.3.11 GPB Utilities

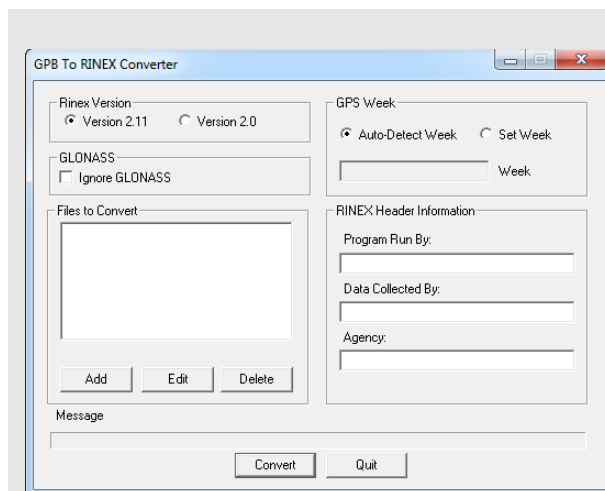
This is available for use with GPB files and includes the following:

Concatenate, Slice and Resample

See *Section 5.3, Concatenate, Slice and Resample Overview* on page 146.

View Raw GNSS Data

See *Section 5.2, GPB Viewer Overview* on page 141.



Convert GPB to RINEX

This utility converts a GPB file into a standard RINEX file, version 2.0 or 2.11.

Rinex Version

Choose between *Version 2.1* and *Version 2.0* format.

GLONASS

If present, GLONASS measurement data writes to the observation file, while the ephemerides write to their own navigation file. This option can be enabled to create GPS-only RINEX files.

Files to Convert

Allows you to select the files that are to be converted.

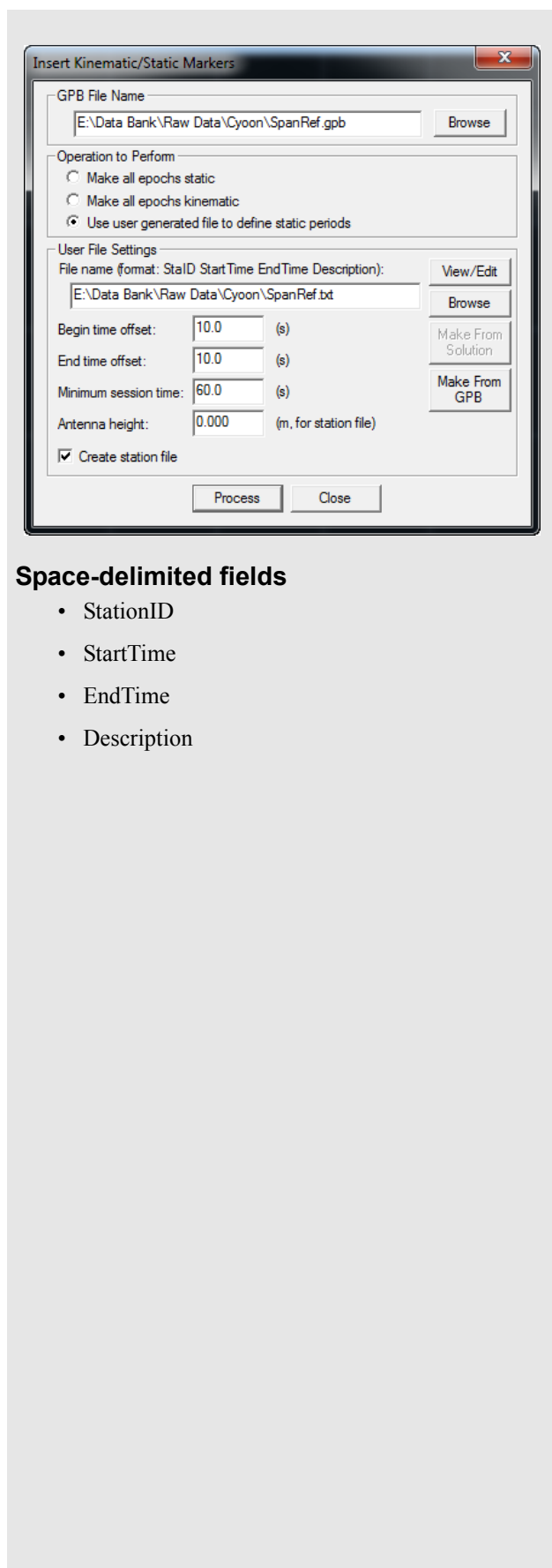
GPS Week

Sets the week number in which the observations were made. If the *Auto-Detect Week* button is selected, then the program determines the week number from the EPP file. Sometimes, an incorrect week number is output to the EPP file during the conversion from a raw data format. In such a case, you must manually enter the week number via the *Set Week* button.

RINEX Header Information

Several fields are available here for editing. This information is used only for the purpose of being written to the header of the RINEX observation file.

- ✉ Multiple files can be added for conversion. For each file added, you are prompted for a station name, an antenna height, and, if needed, an alternate ephemeris file.



Space-delimited fields

- StationID
- StartTime
- EndTime
- Description

Insert Static/Kinematic Markers

Each epoch in the remote GPB file has its own static/kinematic flag, which is set during data conversion. The conversion options for each receiver can be adjusted within the *Global Options* of each receiver type.

The static/kinematic flag can also be changed after data conversion, either through the GPB Viewer or through this utility. Using this utility is preferred over other methods (adjusting the conversion options or through the GPB Viewer) only if it is desired to input multiple static sessions into a single file. This is because this utility supports reading start and end times from a file.

GPB File Name

Specifies the GPB file to modify.

Operation to Perform

Select *Make all epochs static* or *Make all epochs kinematic* to set the mode for every epoch in the GPB file. Select *Use user generated file to define static periods* to define specific time ranges as being static. This enables the *User File Settings* section on the window.

User File Settings

Converts user-defined time ranges to static mode. The input file containing the definitions of the static periods must contain the space-delimited fields listed in the shaded box.

File name

Click the *Browse* button to locate the input file. The *View/Edit* button allows for the revision and modification of the file.

Begin time offset

The number of seconds added to all user-defined *StartTime* values in the input file.

End time offset

The number of seconds to subtract from all user-defined *EndTime* values in the input file. Only the epochs lying between these adjusted times are converted to static mode. This is to ensure that no kinematic data is incorrectly set to static.

Minimum session time

The minimum number of seconds that a static session must contain to be converted to static mode.

Antenna height

If the *Create station file* option has been enabled, this value is written to the station file for all user-defined static sessions.

Create station file

Writes all static sessions to the station file (STA), regardless of whether an antenna height has been entered.

2.3.12 Remove Processing Files

When processing GNSS data, GrafNav's processor generates many different file types, both ASCII and binary. Many of these files are required by the Export Wizard to export the combined post-processed solution.

After the data processing and export is complete, you can choose to delete some or all of the intermediate processing files generated by GrafNav in order to save hard drive space. All of GrafNav's processing files can be easily be regenerated, if needed, provided the project file (.CFG).

This utility can be used to see how much disk space is being used by different types of files generated by GrafNav, and also to delete them. More information is provided in the shaded box.

2.3.13 Recent projects

Provides a list of recent projects for quick access.

2.3.14 Exit

Exits Waypoint software.

Files that are affected with each **Remove Processing Files** option

Project(s) to Remove

Allows you to select what project(s) you want to delete processing files from.

Current project

Only removes the selected files that are associated with the project that is currently loaded.

All files in

Allows you to select the folder from which you want the selected files deleted.

Selected projects

Allows you to select a specific project whose associated files you want to delete.

Files to Remove

Allows you to select the files to remove from the specified project or folder.

GPS trajectories

Contains the solutions computed during processing.

Additional processing

Includes message logs, static summaries and binary files.

Processing history

Contains information regarding any earlier processing run performed in the project. *Section 2.4.4, Processing History* on page 36 for more details.

Project files

Contains project configurations and processing options.

Html/GE files

Deletes everything in the *HTML* sub-folder for a project. This includes any bitmaps, HTML reports or Google Earth output files.

2.4 View Menu

2.4.1 Project Overview

This window provides a summary of the data in the current project. From here, you can view information regarding the base and remote files, including receiver/antenna types, time coverage, and data gaps.

2.4.2 GNSS Observations

These options are available via *Master* or *Remote*:

View Raw GNSS Data

Opens the master file in *GPB Viewer*.

View Ephemeris File

Opens the EPP file in the internal viewer.

View Station File

Opens the STA file in the internal viewer.

Insert Static/Kinematic Markers

Launches another dialog that can be used to change the static/kinematic flags in the data. This is a convenient way of inputting multiple static sessions if you have the start/end times of each session marked in a text file.

Resample/Fill Gaps using the following options

File Interval

Fills all gaps by resampling using the data interval.

Processing Interval

Fills gaps and lowers or raises the data rate in accordance with the specified processing interval.

Remote File Times

Produces a GPB file with epoch times that match the remote file. Any data gap present in the remote file is also present in the new master GPB file. This method of resampling removes unneeded data logged before, and after, the observation time period at the remote.

-
- ☐ Resampling base station data to a lower interval will add noise to the processed trajectory. This noise is negligible if resampling from an original rate of 5 seconds or less, but can add as much as 1-2 cm of noise if resampling from 30 second data.
-

Disable

Disables the selected master station from being used for processing. You may want to disable individual baselines from a multi-base project when trouble shooting poor multi-base processing results.

Remove

Removes the master file completely from the project.

2.4.3 Forward and Reverse Solutions

GNSS / PPP Message Log

These files display all messages generated by the processing engine. GrafNav outputs a forward message log (.fml) and a reverse message log (.rml). Possible messages reported here are listed in the shaded box.

GNSS Summary

These summary files display some basic processing settings and the statistics for ARTK fixes and static sessions. Other items reported in this summary are listed in the shaded box. See *Section 4.4.1, FML & RML Files* on page 134 for an example of this summary file.

GNSS / PPP Trajectory

GrafNav generates a host of information for each processed epoch. Examples include position, velocity, local level vector, measurement residuals, etc. All of this information is written to the trajectory files. GrafNav produces a trajectory file for each processing direction as well as a combined trajectory file, that is automatically produced after processing both directions.

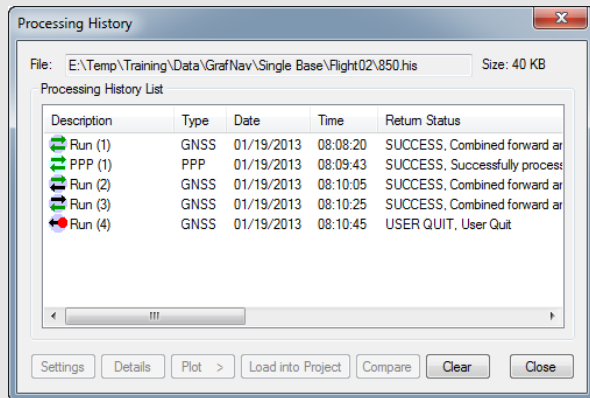
Most of the Q/C plots accessible within GrafNav, as well as the Export Wizard, draw on the information provided in the trajectory files. It is therefore not common to view the contents of these files directly. For an example of a trajectory file, see *Section 4.4.3, FWD, REV, CMB, FSP, RSP and CSP files* on page 139.

Types of messages written to the message log files

- Times at which ARTK was engaged and the reasons for its engagement. These messages are preceded by +++.
- Any satellites with no ephemeris information.
- Epochs of less than 4 common satellites between the master and remote.
- Periods of extremely poor satellite geometry.
- The occurrence of cycle slips. This log gives a time and record of these slips that mean problems in kinematic data.
- Data errors that cause filter resets or the rejection of satellites. These messages are preceded by \$\$\$.
- Entering static and kinematic modes.
- Events resulting from significant changes in the satellites' geometry. These include changes in the base satellite and the rising or falling of satellites above or below the elevation mask.
- The omission of satellites, baselines or time periods from processing.

Static/ARTK summary report items

- Final solutions for all static sessions, as well as the type of solution obtained.
- Time and place at which ARTK engaged successfully, as well as the corresponding statistics. Such information is useful for evaluating whether or not ARTK resolved ambiguities correctly.
- Master station coordinates, antenna summary for base and rover, and the processing mode.
- Satellite usage information pertaining to static sessions.
- Slope, horizontal and corrected ellipsoidal distances for all static sessions.
- Program completion information.



Processing history view options

Settings

Brings up the processing settings used for the selected run.

Details

Displays more information about the selected run, including the following option for the configuration file.

Plot

Accesses the *Combined Separation*, *Estimated Position Accuracy*, *Quality Factor* and *Float/Fixed Status* plots for the selected run. Be aware that if processing was not performed successfully in each direction, certain plots can be unavailable or incomplete. This feature is very useful for comparing different runs.

Load into Project

Loads the processing settings for the selected run into the current project. You are prompted to back-up the current project to a BAK file.

Compare

Compares two configuration files that are selected by holding down the *Ctrl* key. This feature is useful for determining the difference between the settings used for two runs.

Clear

Deletes the entire processing history.

2.4.4 Processing History

This feature displays the processing history in a chronological list. It contains the date and time when each run was performed, as well as the user's initials if this was provided when processing. It also contains a description of the run, including the directions being processed, the processing settings and the return status.

The processing history can be used to restore settings from a previous run and compare processing settings between processing runs. A limited list of plots is also available for each processing run. View options in the *Process History* box are listed in the shaded box.

2.4.5 Processing Summary

This file provides a statistical summary of the processing results. It can be used for reporting and quality checking purposes. A list of the items reported in this file include:

- Solution type (forward/reverse/combined)
- Summary of the number of epochs processed, missing, and epochs with poor measurement residuals
- Phase, code and Doppler RMS
- The RMS of the forward/reverse position separation, including separate statistics where both solutions are fixed.
- Breakdown of quality number percentages
- Percentages of standard deviations that fall within given intervals
- Percentage of epochs with very poor satellite geometry (DD_DOP > 10)
- Baseline distance summary

The *Processing Summary* can be added to the end of an output text file created through the *Export Wizard*. See *Section 2.7.5, Export Wizard* on page 72 for information about the *Export Wizard*.

2.4.6 Features

The *Feature Editor* window lists all of the features loaded into the project. If the data has been processed, a summary of processing quality is also displayed. In addition to viewing features, the feature editor can also be used to:

- Edit station feature names, time-tags, as well as antenna heights and models. For camera marks, the line number can be inserted into the *Desc/Info* field.
- Re-number stations and camera event marks.
- Disable features so that they are not displayed or exported.

The shaded box has a list of the columns that are displayed.

☒ Changes made to stations are saved automatically to an NST file. To revert back to the original station information, use *File | Load | Station File*.

Displayed in the *Features Editor* window

Name

The name of the feature. The symbol next to the name indicates the type of feature loaded. Examples include camera marks and stations. The symbol appears grey if the feature has been disabled.

Time

This is the feature's GPS capture time. To show the time in HH:MM:SS, select *Show HMS*.

Q

Reports the quality number. Quality numbers range from 1 to 6.

- 1 represents a fixed integer solution with good satellite geometry
- 2 & 3 represent either fixed integers with marginal geometry or converging float solutions
- 4 & 5 indicate qualities similar to DGPS
- 6 represents a C/A only solution

The quality number is only meant to communicate, at a high level, the overall processed data quality. For more information, access GrafNav's quality control plots.

Std(m)

Combined standard deviation of the north, east and height components, including additive PPM based error.

Fix

Shows the ambiguity status of the feature's solution:

Y = fixed integer **N** = float solution

Azimuth

Azimuth, in degrees-minutes-seconds, from previous feature to current feature.

Dist(m)

Distance, in metres, from previous point to current point.

Dt(s)

Time difference, in seconds, between current and previous point.

Height

Height, in metres, of the feature. This is normally an ellipsoidal height, but if the master station height was entered as orthometric, then this height is more orthometric. Use the *Export Wizard* to get the exact orthometric height. For stations, like STA and GIS, with antenna heights, this height is of the monument and not the antenna.

AntHgt

The height of the antenna above the monument. Camera marks do not have an antenna height, and so *N/A* is displayed.

Desc/Info

Describes the feature or line information for the camera mark.

Options in the *Features Editor* window

Remarks

Remarks field.

Add Station

Lets you manually add a station. Also add stations by right-clicking on epochs in the map window. You might want to add stations to static sessions that have none because static sessions cannot handle a varying antenna height and a station can.

Remove

Removes the selected stations. Multiple stations can be selected and removed. You might consider disabling a feature instead of deleting it.

Edit

Edits the station name, time-tag, description and antenna height of the selected feature.

Select All

Selects all features.

View Info

Shows processing information for any selected feature enabled during processing.

Global Edit

Make changes to multiple selected features. Modifications can be made to the antenna heights, descriptions, camera line information, remarks and drift/crab angles.

Re-Number

Re-number a selection of stations. Numbering can be performed starting from the bottom or the top of the list. You can specify the starting number and the increment value. To decrease numbers, use a negative number.

Move to Static

This feature is used to assist in the quality control of surveys where multiple short static sessions are collected in challenging GNSS signal environments. When used, it allows you to see the difference between the forward and reverse solution for each static session in your survey when exporting from the Wizard.

An example of an application that may use the Move to Static feature is seismic surveying. Move to Static requires that a station mark be present within each static session.

✉ *Global Edit, Re-Number and Move to Static* work with multiple features selected. To select a continuous block, hold down the *Shift* key while clicking on features. To select individual features, use the *Ctrl* key.

The shaded box contains a list of the options that are available with the buttons on the right-hand side of the *Features Editor* window.

2.4.7 Objects

Select *View | Objects | All* to access the Object Menu window. This window provides access to ARTK fixes, static sessions, features/camera marks, epochs, master stations and RTK data if present. The *Object Menu* can also be activated by right-clicking on an epoch in the map window. This displays the features and epochs around the selected epoch.

The options that are available with the buttons on the right-hand side of the window are listed in the shaded box.

Static Sessions

A remote GPB file may contain multiple static sessions. These can either be separated by data gaps, if the receiver is turned off when moving to a new station, or kinematic marks if a "stop and go" style of survey is being performed.

By default, if GrafNav detects a data gap larger than 120s between static sessions, they are treated as separate occupations. This is a setting that can be controlled within GrafNav's *Fixed Static* tab.

The default antenna height and model applied to every static session in the file is the same as that entered within the *Remote* tab when creating a project. Antenna models and heights can be adjusted for individual static sessions by accessing the *ARTK/Static* component of the Object Menu. This can be accessed through *View | Objects | ARTK/Static*.

Options available in the *Objects Menu* window

View

Brings up the *Object Info* message box for the selected object.

Edit

Edits the station name, description and remarks for the current selection. If a master station is selected, this allows you to edit the coordinates and antenna height.

View/Edit GPS

Displays the following list of options. You must have selected an epoch to use these options.

View Raw GNSS Data

Opens the master file in GPB Viewer

View Ephemeris File

Opens the EPP file in the internal viewer.

View Station File

Opens the STA file in the internal viewer.

Insert Static/Kinematic Markers

Opens a menu to insert static/kinematic markers in the file.

Remove

Removes the master file from the project.

Add as Station

Lets you manually add a station. The station's time is automatically set to the time of the selected object.

Initialize Remote

Lets you to fix the remote's position at the time of the selected object. This will only work on objects with valid solutions.

Engage ARTK

Forces the software to engage ARTK at the selected object's time.

Add to Favourites

Adds the object's solution to the list of *Favourites*.

Set Start Time

Uses the selected object's time as the start time for GPS processing.

Set End Time

Uses the selected object's time as the end time for GPS processing.

Find on Map

Finds the selected epoch on the map window.

Go to FML

Searches the forward GNSS differential message log for a record closest to the time of the selected object.

Go to RML

Searches the reverse GNSS differential message log for a record closest to the time of the selected object.

Override values

Point Name

Allows you change the station's name.

Antenna Information

To edit the antenna height and/or antenna model for the static session, click the *Change...* button.

Fixed solution usage settings

Never

A float solution is used for the static sessions.

Always

A fixed integer solution is attempted for the static sessions.

Only if distance and time OK

A fixed integer solution is attempted if the baseline distance and session length are within the tolerances applied in the *Fixed Static* tab of the GNSS processing options.

Edit Static Sessions

Select a static baseline from the *Object Menu* and click the *Edit* button to display the *Edit Static Session* window. The options in this window allow you to change the station name, antenna height, antenna model and fixed static processing options for the static session.

Time Range

Displays information regarding the static session.

Start/End

Displays GPS seconds, GPS week number, GMT time and date (*mm/dd/yyyy*) for the beginning and end of the static session.

Length

Displays the difference between the start and end time.

Point Name and Antenna Height

Displays information regarding the observed point name and antenna height.

Automatic determination

Applies the antenna height and point name from the global remote settings.

Override with these values

Allows you to manually enter the parameters that are listed in the shaded box.

Fixed static settings

Customizes the conditions and settings for the use of a fixed static solution.

Fixed solution usage

Allows you to override the global tolerances for distance and length within the *Fixed Static* tab. More information about these options is in the shaded box.

Use global fixed static options

Allows you to customize the fixed static processing options for the static session.

2.4.8 ASCII File(s)

The *View ASCII File(s)* option allows you to view any of the ASCII files generated by the software using GrafNav's ASCII file viewer. Examples of these files include the following:

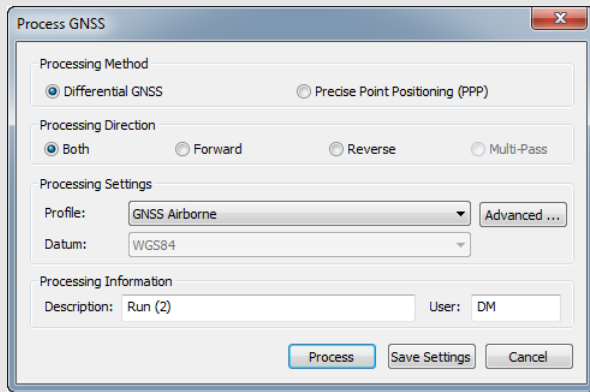
- Epoch Solutions (FWD, REV and CMB)
- Message Logs (FML and RML)
- Static Summaries (FSS and RSS)
- Station Files (STA)
- Ephemeris Files (EPP)
- Configuration Files (CFG).

2.4.9 Raw GNSS

This option launches the GPB Viewer. The GPB viewer allows the viewing and editing of raw GNSS data that has been converted to Waypoint's format. This viewer is also launched from *File | View | Raw GNSS Data*, or by double clicking a converted GPB file within Windows Explorer. See *Section 5.2, GPB Viewer Overview* on page 141 for more information.

2.4.10 Current CFG File

This option opens a GrafNav project file (.cfg) within GrafNav's ASCII viewer. The CFG file contains all of the processing settings in a project.



Process direction options

Both:

When processing *both* directions, independent forward and reverse solutions are processed and automatically combined. This method of processing is the default for differential processing.

Combining forward and reverse solutions maximizes solution accuracy and assists in quality control. Depending in part on baseline length, satellite geometry and number of satellites available, forward and reverse solutions may achieve different solution types (fixed/float) for different parts of the survey.

When both directions are combined automatically after processing, GrafNav applies inverse variance weighting to ensure the direction with the lower estimated errors receives the most weight in the final trajectory.

Position differences between forward and reverse directions can be accessed from the *Combined Separation* and *Combined Separation (fixed)* plots after processing. The latter plot shows the differences in positions only where both have fixed integer solutions. This plot will help detect incorrectly fixed ambiguities.

Forward and Reverse:

Changing the processing direction to *forward* or *reverse* is normally done only if a problem is detected after processing *both* directions. The *Advanced* dialog can be accessed to customize processing options prior to reprocessing. Forward and reverse solutions are automatically combined when processing either forward or reverse.

Continued on following page...

2.5 Process Menu

2.5.1 Process GNSS

The Process GNSS dialog is intended to provide a one page startup where the processing method (differential and PPP), processing direction, and processing options can all be conveniently accessed.

Processing Method

Differential GNSS

Differential processing can be selected if base station(s) have been added to the project. This method of processing provides access to ARTK, where carrier phase ambiguities are fixed for high accuracy applications.

Precise Point Positioning (PPP)

PPP is an autonomous positioning method where data from only one receiver is used. If base station data has been added to the project, it will not be used when processing PPP. By design, both differential and PPP trajectories can be processed within the same project without over-writing each other.

GrafNav's PPP processor requires dual frequency data as well as precise orbit and clock files. GrafNav will automatically attempt to download precise orbits and clocks if the *Process* button is selected prior to adding this data to the project.

Processing Direction

See the shaded box for a complete description of the processing directions available.

Processing Settings

Profile

Processing profiles are available for aerial, ground vehicle and marine applications. These profiles load processing settings that have been found to work well for each application, including changes to the default elevation mask, ARTK options, measurement weighting and more.

Processing profiles are particularly helpful for new users, as adjusting individual processing settings from the *Advanced* options are often unnecessary in order generate a high quality result. For advanced user's, processing settings can be created or customized.

During decoding, GrafNav's pre-processing checks use the unprocessed position decoded in the raw GNSS data to detect the processing environment (aerial, ground vehicle or marine). The detected environment is written to the header of the GPB file, allowing GrafNav to automatically load a processing profile the first time you access the

Process GNSS dialog. This is done to help new users generate a high quality result with as little user intervention as possible.

Advanced...

Depending on the processing method selected (differential or PPP), selecting *Advanced* provides access to all available processing settings.

Datum (PPP processing only)

The processing datum is directly accessible from the *Process GNSS* dialog for PPP processing only. In differential processing, base station coordinates and the project datum should be set when adding base station data to the project.

PPP is however an autonomous positioning method which does not use base station data. Thus, the processing datum is treated like a processing option.

GNSS data can be processed in any global datum such as WGS84, ITRF, ETRS89, and NAD83. If you require results in a different datum, a datum transformation can be applied within the Export Wizard.

Processing Information

Description

The processing description automatically appears as *Run (1)* for the first differential processing run or *PPP (1)* for the first PPP processing run. In order to distinguish each processing run within the processing history (accessible from *View | Processing History*), the counter within the parentheses automatically increases each time a processing run is performed. The description of the processing runs can be edited (optional).

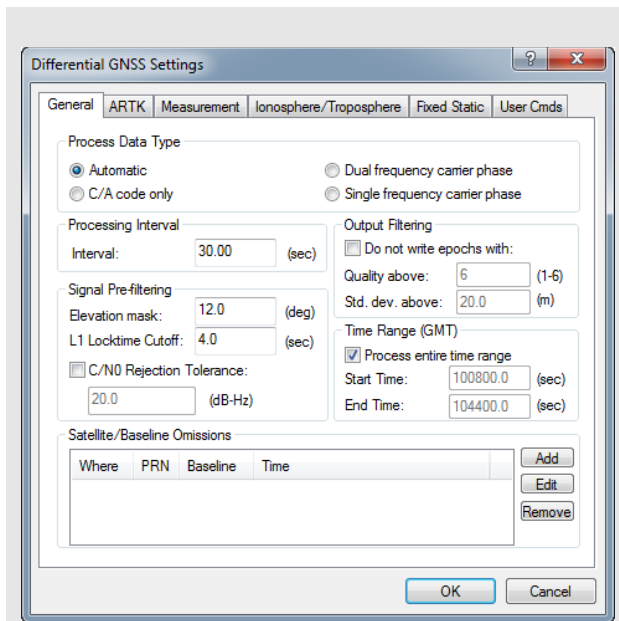
User

You can enter your name or initials here. This is shown in the processing history (*View | Processing History*) and can be helpful if multiple users will be processing the same data on the same computer.

Multi-Pass:

This method of processing is available only for PPP. This is because it is a method of processing designed to maximize float solution convergence. This is not normally a consideration in differential processing due to ARTK, where carrier phase ambiguities are fixed.

When choosing multi-pass processing, forward and reverse solutions are not independent. Rather, the data is processed three times sequentially (forward, reverse and forward again). After each direction finishes processing, the converged Kalman filter error states are applied to the next processing direction. The benefit of this method of processing is that float ambiguity convergence is maximized, producing in some cases near fixed integer solution quality. This method of processing is most effective on shorter surveys (less than four hours).



Signal Pre-filtering Options

Elevation Mask

Satellites below this elevation (relative to the horizon) are ignored. Common elevation masks for differential kinematic processing are 10-12 degrees. Static processing generally benefits from a higher elevation mask. 15 degrees is suggested.

Low elevation signals are more affected by multipath and tropospheric error, and are more likely to be affected by cycle slips due to signal blockages and/or signal attenuation by the antenna. Thus, pre-filtering low elevation signals is generally beneficial to post-processed accuracy.

L1 Locktime Cutoff:

This is the number of seconds that continuous carrier phase tracking is required before measurements will be used. Lowering this value will help to maximize GNSS position availability following a total loss of carrier phase lock. However, using low values increases the likelihood of an incorrect ambiguity fix. This is because the quality of carrier phase measurements may be suspect within the first few seconds the receiver achieves carrier phase lock.

C/N0 Rejection Tolerance

Most often, pre-filtering GNSS signals by elevation mask and L1 locktime cutoff is effective. For specialized applications, introducing additional pre-filtering based on the signal to noise ratio can also be effective.

This option is not engaged by default as not every receiver provides a C/N0 value, and different receivers may output this value at different stages of signal processing. Care should be used if applying this option.

General

Process Data Type

Defines the type of data used for processing.

Automatic

Detects dual frequency, single frequency or code only receiver data. As only common data can be processed between the remote and base station(s), dual frequency carrier phase will be applied only if all data is detected to contain dual frequency measurements.

C/A code only

Only C/A code measurements are applied in this method of processing which is associated with accuracies on the order of several meters.

Dual frequency carrier phase

Dual frequency processing uses L1 and L2 data for the highest possible post-processed accuracies. Ambiguity resolution is much faster, more reliable and possible at longer baseline lengths than single frequency processing. For long baselines (>7 km by default), ionospheric processing is automatically engaged, helping to preserve post-processed accuracy with increasing baseline length.

Single frequency carrier phase (Differential GNSS processing only)

Single frequency processing uses L1 measurements only. While ambiguity resolution can still be successful on very short baseline lengths, this method of processing is generally associated with decimeter level applications. As the ionospheric error cannot be directly measured and removed, as in dual frequency processing, post-processed accuracy quickly degrades with increasing baseline length.

Processing Interval

The data rate of the remote GPB file is used as the default processing interval. However as only common data between the base station and remote can be processed, you will need to ensure the base station(s) were also logged or resampled to the same interval in order to output a trajectory at this interval.

GrafNav's pre-processing checks will warn you if the master data rate is detected to be less than the remote.

Signal Pre-filtering

These options are listed in the shaded box.

Time Range (GMT)

Defines the time range to be processed. If the *Process entire time range* option is enabled, GrafNav processes starting at the first epoch the master and remote have in common and ending at the last. To limit the scope of processing, use the *Begin* and *End* fields. The default time system is GPS seconds of the week (0-604800).

Output Filtering

Do not write epochs with:

If enabled, these options prevent epochs that do not meet requirements from being displayed to the map window after processing and from being written to the trajectory files. GrafNav's Export Wizard can also be used to filter results by quality number and standard deviation, thus output filtering does not need to be performed at this stage.

Satellite/Baseline Omissions

GrafNav's pre-filtering options will often remove noisy or problematic data prior to the processing stage. During processing, GrafNav's automatic outlier detection routines work to automatically fix errors when large measurement residuals are detected. Failing all of this, if a problematic measurement or satellite can be identified, usually from examining the forward or reverse message log files, the *Omit Satellite Info* dialog can be accessed to manually enter satellite omissions.

Satellites to Omit

All Satellites

Disables all satellites from being used.

Only specified satellite

Disables individual satellites.

Baselines to Omit

Omit satellite for all baselines

Applies the satellite omission to all baselines in the project.

Only selected baseline

Applies the satellite omission only to the specified baseline (applies to multi-baseline projects only).

Time Period

Omit for entire data set

Applies the omission to the entire processing time range.

Use specified time range

Applies the omission to a specific time period, entered in GPS seconds of the week.

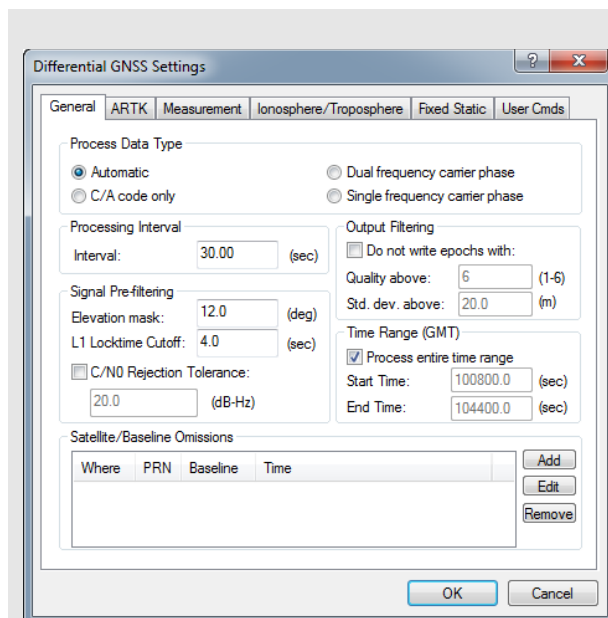
Where to Omit

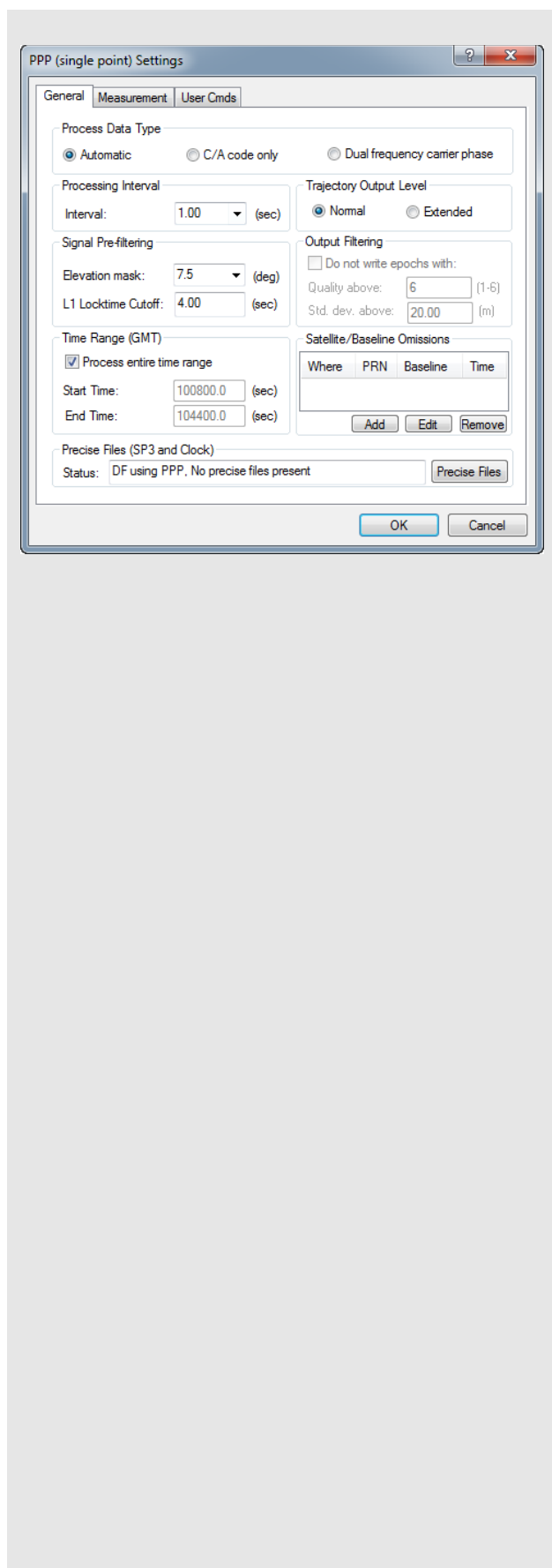
From processing

Applies the omission to all types of processing.

From ARTK/Fixed-Static only

Applies the omission only during ambiguity resolution.





Precise Files (SP3 and Clock) (PPP processing only)

Precise ephemeris (orbit) and clock files are required for PPP processing in order to correct for meter level errors. If processing PPP, the *Precise Files* button can be used to add previously downloaded files or to automatically download the required data.

-
- ✉ It is not required to add the precise orbit and clock files through this dialog. They will be automatically downloaded if the files are not present and *Process* is selected from the main processing dialog.
-

Precise ephemerides are optional for differential processing, as most of the orbital error is removed in differential processing. However, projects that involve large distances between the remote and base station(s) can benefit from the inclusion of the precise ephemeris. For differential projects, precise ephemerides can be added or downloaded from *File | Add Precise Files*.

ARTK Options (Differential GNSS processing only)

ARTK (AdVance RTK) is NovAtel's method of resolving integer carrier phase ambiguities in kinematic mode. ARTK should be engaged in high accuracy applications, whenever cm level results are required.

Dual-frequency ARTK provides fast, reliable, and robust performance. However, in high multipath environments or where the satellite geometry is relatively poor, the possibility of an incorrect ambiguity fix exists. This is why it is important to access GrafNav's quality control plots which will help detect errors.

- ☒ Both single and dual-frequency ARTK require at least 5 satellites, but 6 or more are preferable.

General

Criteria for accepting new fixes

ARTK can be used in *Default* or *On engage only* modes. These modes are described in the shaded box.

Quality acceptance criteria

This is the confidence level required in residual testing for an ARTK fix to be accepted. Using lower quality acceptance criteria increases both the likelihood of achieving a fix and the possibility the fix may be suspect. Conversely, increasing the quality acceptance criteria helps reduce the likelihood of incorrect ambiguity fixes, but also the chance that no fix is achieved when conditions are marginal for ambiguity determination.

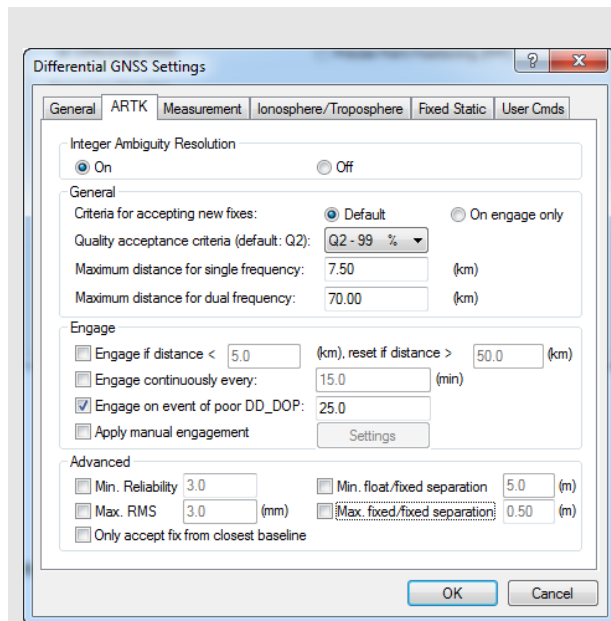
The default criteria applied is Q2 (99%). This is considered a good starting value for all applications. In general, aerial applications benefit from more strict tolerances as the GNSS signal conditions are not challenging. Using too strict a tolerance in ground vehicle applications can result in float solutions only for a large percentage of the trajectory

The quality acceptance criteria provides a level of control over ARTK performance, however advanced users can also apply additional thresholds such as the minimum reliability, maximum RMS, and other thresholds listed in the *Advanced* section.

Maximum Distance

The distance tolerance for engaging ARTK in both single and dual frequency can be defined here. The default values applied are high, and therefore are more often lowered than increased.

If your project involves a long flight to or from the project area, and your base station is operating in the project area, it is generally beneficial to lower the distance threshold to 30 km or less. This will prevent



Integer Ambiguity Resolution processing option settings

On

Engages ARTK for both single and dual frequency data processing.

Off

Disables ARTK. This will produce a float solution.

Criteria for accepting new fixes

Default

When ARTK is used in default mode, it is constantly re-checking its solved ambiguities when the satellite geometry changes (i.e. when new satellites come into the solution or when individual satellites are lost). New fixes are accepted if they are different by a minimum of 1.2 cm + 0.8 PPM. Thus it is possible, even under open sky conditions where no loss of lock occurs, that ARTK will reengage itself several times as new satellites come into the solution or as the satellite geometry changes.

Using ARTK in default mode is thus mostly preferred for ground vehicle applications, as this method provides a high level of solution accuracy over the entire length of a trajectory. As it is likely ARTK re-engages many times during a survey, even where no loss of lock occurs, the likelihood of small position jumps when new fixes are accepted is high. This is not however a problem for the majority of ground vehicle applications. Loading the *GNSS Ground Vehicle* processing profile ensures that ARTK is used in *Default* mode.

Continued on the next page...

On engage only

This method ensures ARTK engages only at startup, when a complete loss of lock occurs, or after a period of very poor satellite geometry. This method is generally preferred for aerial applications as it ensures that new ambiguity fixes are not accepted in the middle of a flight line, where position jumps can be problematic.

A new option in version 8.50, the *fixed/fixed separation threshold* found in the *Advanced* section, allows control of the maximum allowable position jump when ARTK accepts a new fix.

ARTK from engaging itself unnecessarily far from your project area, which increases the likelihood of an incorrect ambiguity fix.

Engage Options

These options control when ARTK is engaged.

Engage if distance < tolerance1, reset if distance > tolerance2:

The first tolerance is used to automatically re-engage ARTK on approach to any new base station. The remote must exceed the second tolerance for ARTK to re-engage when re-approaching the same base station. This option, specifically the first tolerance, is useful in multi-base projects where there are multiple project areas.

Engage continuously every:

Engages ARTK at regular intervals. This option does not check other criteria, such as baseline length or data quality. Thus, it should not be used for aerial applications. It is intended for use in slow moving or monitoring applications.

Engage on event of poor DD_DOP:

It is possible to maintain a fixed integer solution through an event which causes poor satellite geometry, provided carrier phase lock is maintained on four or more satellites.

However, it is good practice to re-engage ARTK following the event. When satellites are re-acquired, their carrier phase ambiguities are not automatically re-established as fixed integer solutions. Thus, it is possible that following a period of poor geometry, more satellites in the solution have float ambiguities than fixed. This will not necessarily result in degraded accuracy, but re-establishing all satellites with fixed ambiguities is generally beneficial to maintaining high accuracies.

Apply Manual Engagement

A manual ARTK engagement forces GrafNav to re-establish carrier phase ambiguities. Introducing a manual engagement is one technique to recover from an incorrect or drifting ambiguity fix. These instances (incorrect or drifting ambiguity fixes) can be identified from the forward/reverse separation plots.

Advanced

These options provide advanced users more control over ARTK performance and more tools when reprocessing problematic surveys. Each of the advanced options are off by default, however can be individually enabled if needed.

Min. Reliability:

The reliability of an ARTK fix is the ratio of the second best RMS and the best RMS. It indicates how much better the best solution is from the second best solution. High reliability values indicate the best RMS is significantly better (lower) than the second best RMS, and thus a high degree of confidence can be placed in the solution. This option provides direct control over the minimum reliability ARTK will accept as a pass.

Max. RMS:

An RMS is computed for every possible ARTK fix within a given search area. This RMS, output by GrafNav in units of mm, represents the mathematical fit of the solution or how well the carrier phase measurements agree with each other. Low values (mm level or sub-mm) represent well fitting solutions, or measurements that agree very closely. Large values (several mm or cm level) indicate poorer fitting solutions that are more suspect. This option provides direct user control over the maximum allowable RMS for an ARTK fix to be considered a pass.

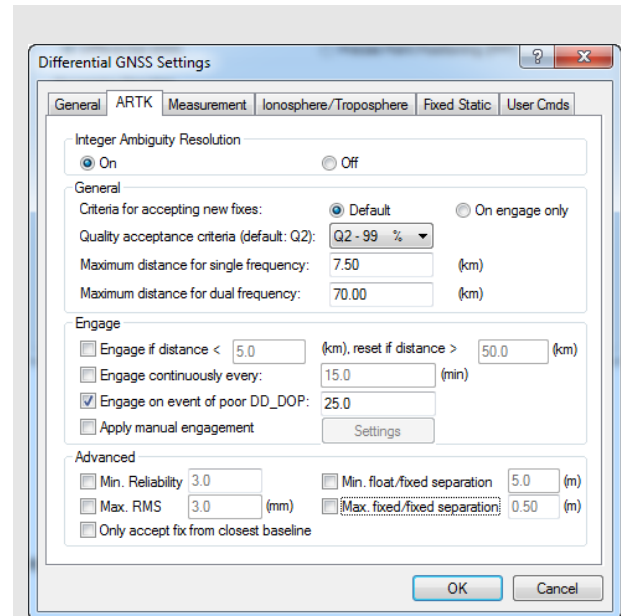
Max. float/fixed separation:

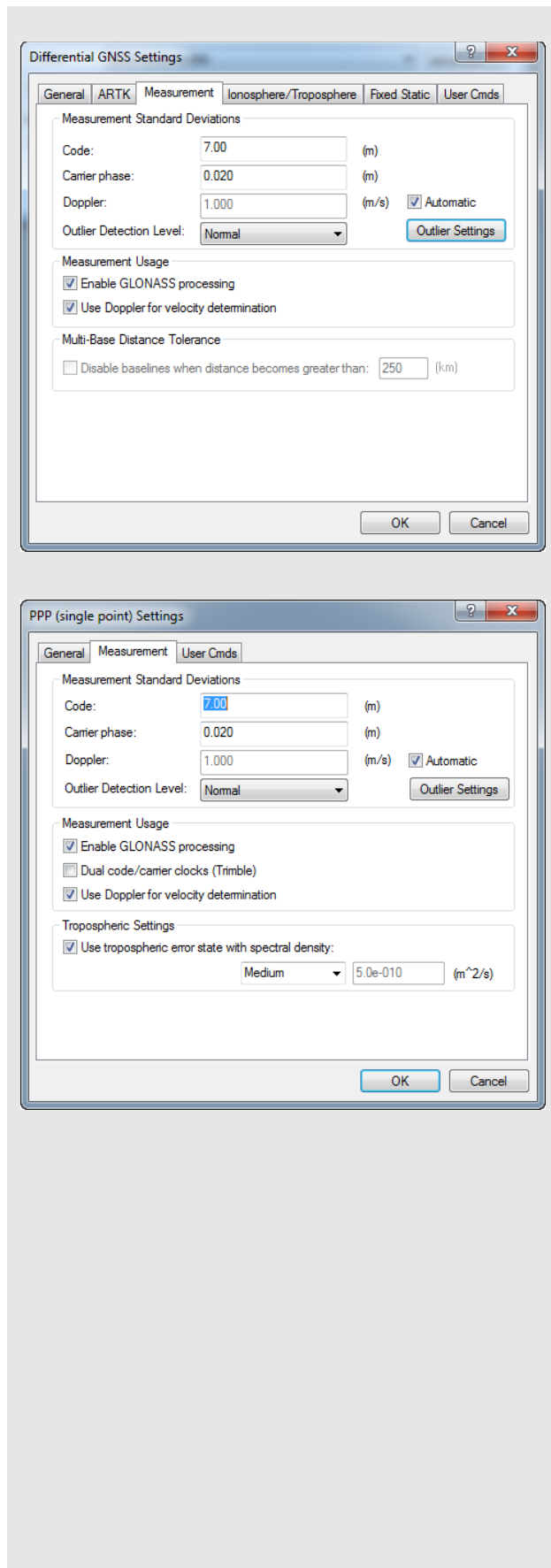
Using this option forces the float solution to converge within a specified distance prior to a fix being accepted. It is recommended to keep this value high (10 m to 15 m) for ground vehicle applications as often only several seconds are used to establish an ambiguity fix. In these applications, large differences are expected between float and fixed solutions.

However in aerial surveys, this option can essentially limit the speed at which ARTK engages. Aerial surveys do not benefit in the same way as ground vehicle surveys in regards to fast ambiguity resolution. That is, aerial surveys often have the luxury of using more data, or taking more time, to ensure the ambiguity fix is correct. In most aerial surveys, correct ambiguity resolution is much more important than fast ambiguity resolution and this option can be used to ensure a certain level of convergence prior to accepting a fix.

Max fixed/fixed separation:

This option is of significance when ARTK is used in *Default* mode. In this mode, ARTK is constantly re-checking its carrier phase ambiguities as the satellite geometry changes. If a new set of ambiguities are solved that produce a position difference greater than $1.2 \text{ cm} + 0.8 \text{ PPM}$ relative to the current set of fixed integer carrier phase ambiguities, it is accepted. This option provides an advanced user the ability to limit the allowable size of the position jump when accepting new fixed ambiguities.





Measurement

Measurement Standard Deviations

Sets the measurement standard deviations applied to code, carrier and Doppler measurements.

Code

Controls the measurement weighting applied to the double differenced C/A measurements. Regardless of what value is entered here, if ARTK is used to fix integer carrier phase ambiguities, the C/A measurement standard deviation will not impact results. This is because when ambiguities are fixed, the strength of the solution comes from the carrier phase. The C/A measurement weighting can affect float solution convergence and is one of the most effective setting available for optimizing float trajectories.

Carrier phase

Controls the measurement weighting applied to the double differenced carrier phase measurements. This value is automatically adjusted upwards if ionospheric processing is engaged. Also, an additive PPM value is applied to account for increased noise on long baseline lengths. In general it is recommended to leave this value at the default of 2 cm. However, it may need to be increased in certain applications (such as, when ionospheric activity is particularly high).

Doppler

Doppler is the instantaneous rate of change of the carrier phase signal as measured in the receiver. Doppler is used to calculate instantaneous velocity. GrafNav assigns a conservative measurement weighting of either 1.0 m or 0.25 m depending on the receiver manufacturer. GrafNav uses a very conservative weighting as the quality of Doppler measurements vary significantly from one receiver manufacturer to another.

Outlier Detection/Rejection

GrafNav attempts to automatically reject satellites or measurements when large measurement residuals are detected. If a large residual is detected, GrafNav systematically rejects each satellite individually and recalculates the position and residual. If the new residual is significantly lower than the original residual, the satellite is automatically removed from the solution at that epoch. GrafNav's sensitivity to high measurement residuals is controlled through this setting.

Measurement Usage***Enable GLONASS processing***

If GLONASS is present at both the base and rover (for differential processing), inclusion of GLONASS measurements is controlled with this setting. If processing PPP, GLONASS measurements can be used only if the precise clock and orbit products downloaded contain GLONASS values.

Dual code/carrier clocks (PPP only)

This option engages the use of separate clock states for the code and carrier measurements. Whether this option should be engaged is completely dependent on receiver design. It is most often needed for Trimble receivers, so this option is automatically engaged if the remote receiver is detected to be a Trimble. If this option is not used when needed, the typical result is Kalman filter resets even if the data is of very high quality.

Use Doppler for velocity determination

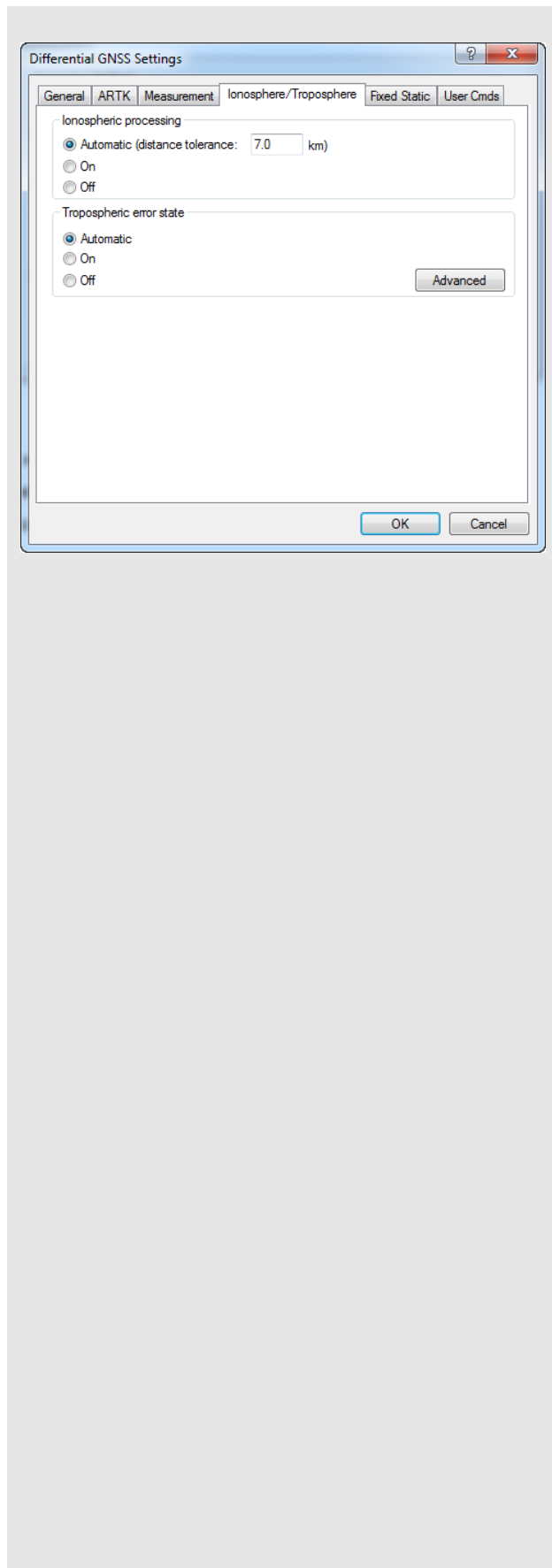
If engaged, Doppler is used to derive instantaneous velocity. If many Doppler measurement errors are output to the GrafNav processing dialog, it may indicate the Doppler measurement quality of your receiver is very poor. In this case, it is recommended you disable this option and calculate the velocity using a carrier phase model.

Multi-Base Distance Tolerance (Differential processing only)

This option is used to automatically disable base stations according to baseline length. This is an effective means of managing base station data use in very large scale aerial projects.

Tropospheric Settings (PPP processing only)

As no base station data is used to reduce correlated errors, such as tropospheric delay, this must be solved as an additional state within the PPP filter. The tropospheric spectral density controls how fast GrafNav allows the tropospheric state to change. *Medium* is suitable for most projects, but *High* may work better if very fast and frequent changes in elevation are expected in your survey. *High* allows the tropospheric conditions to change more rapidly within the filter.



Ionosphere/Troposphere (Differential GNSS processing)

Ionospheric Processing

Ionospheric processing requires dual frequency data. It helps to maintain GNSS positioning accuracy with increasing baseline length. The ionosphere can be a significant error source for L1 only processing as it is highly unpredictable and can change rapidly.

Ionospheric processing essentially removes the ionospheric delay as an error source, however does so at the cost of higher measurement noise. Thus, best results are achieved on short baseline lengths when ionospheric processing is disabled. However when the baseline distance becomes large, the benefits of correcting for the ionosphere out-weigh the increased noise and best results are achieved when enabling this option.

In order to handle both scenarios, GrafNav has an *Automatic* setting that will engage, or disable, ionospheric processing depending on the length of the baseline detected in the project. Prior to processing, the unprocessed positions in the remote GPB file are compared with the base station position. If more than 10% of the trajectory exceeds the distance tolerance, ionospheric processing is engaged.

In addition to *Automatic*, ionospheric processing can also be explicitly turned *On* or *Off*.

Tropospheric Error State

Unlike ionospheric error, tropospheric error cannot be directly observed and removed using dual frequency measurements. This is because the troposphere is non-dispersive at GPS frequencies and affects L1 and L2 equally. GrafNav uses a Saastamoinen model to estimate the tropospheric delay at the base and remote. However regardless of what model is applied, tropospheric error is largely removed in differential processing as it is a correlated error on short baseline lengths.

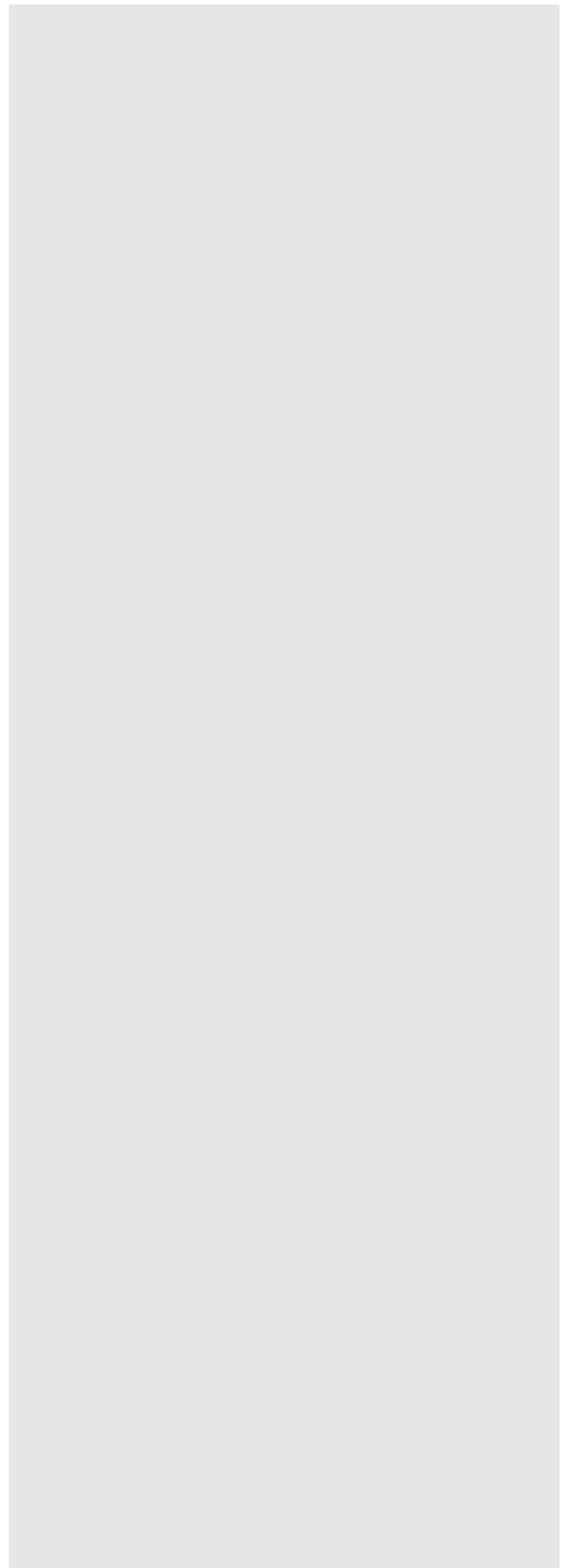
As the baseline length increases (to ~150 km or more) and/or where there is a significant height difference between the base and remote (~10,000 ft), residual tropospheric error can easily become the largest error source; reaching magnitudes as much as 30 cm in some cases.

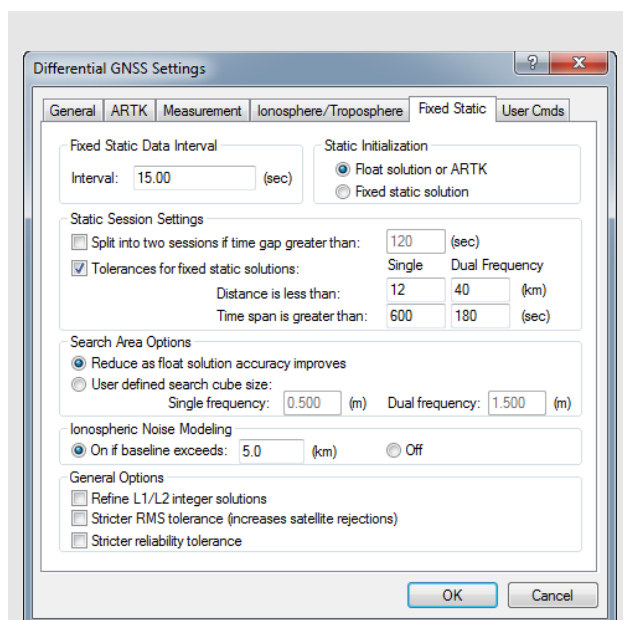
In order to reduce the tropospheric error under these conditions, GrafNav leverages the ability of the Precise Point Positioning engine to observe the actual tropospheric delay at the base station. In PPP, tropospheric error is observed as an additional Kalman filter state. Hence, GrafNav first solves the actual tropospheric delay at the base station and then, as a second step, applies this information in differential processing.

The advanced tropospheric state can reduce residual tropospheric significantly, further preserving GNSS post-processing accuracy as baseline length increases.

The *Automatic* setting will automatically engage this option if 10% or more of the unprocessed positions are over 150 km from the base station OR if 10% of the survey is detected as being flown in excess of 3000m, or 10,000 feet above the base stations. In both cases, a minimum of two hours of data is required for this option to automatically engage, as it can perform poorly on short data sets where there is insufficient data to provide a well converged solution.

In addition to *Automatic*, the tropospheric error state can be explicitly turned *On* or *Off*.





Static Initialization Options

Float solution or ARTK

This setting disables fixed static processing in GrafNav. ARTK, if enabled within the ARTK tab, will be used to fix carrier phase ambiguities regardless of whether the data is processed as static or kinematic.

Fixed static solution

This setting ensures that the fixed static solution, not ARTK, is used to resolve carrier phase ambiguities for static sessions. Although both solutions can produce mm or cm level results, fixed static solutions are generally more accurate as more data is used. ARTK should be used for shorter occupations, as fixed integer solutions require an appreciable change in satellite geometry in order to be reliable (generally, 15-20 minute or more).

Search Area Option settings

Reduce as float solution accuracy improves

This option reduces the fixed static search area as the float solution converges. For long occupations (several hours), this often results in computed reliability values being displayed as N/A if only one possible fixed integer solution was found in the search area.

User defined search cube size

Using a fixed search area, as opposed to reducing the search area as the float solution improves, helps ensure that a reliability value is computed for fixed solution. Practically speaking however, this will not help or hinder the accuracy of the solution.

Fixed Static

Fixed Static Data Interval

The recommended interval for fixed static is 15 or 30 seconds. Smaller intervals result in overly optimistic accuracy estimates due to high correlation of carrier phase data and does not improve accuracies.

Static Initialization

The two options are described in the shaded box.

Static Session Settings

These parameters govern how GrafNav processes static baselines. The options for this setting include the following:

Split into two sessions if time gap greater than:

If selected, GrafNav treats time gaps greater than the tolerance as an indication of a new station occupation.

Tolerances for fixed static solutions:

Allows you to specify distance and time tolerances to prevent unintentional static fixes on very long baselines or short time periods.

-
- ☒ For these settings to be applied, *Fixed static solution* has to be selected on this tab.
-

Search Area Options

The search region size can be controlled with the options described in the shaded box.

Ionospheric Noise Modeling

The ionospheric noise model controls how the L2 measurements are treated in the fixed solution. Due to anti-spoofing, L2 can be noisier than L1. So, on shorter baselines, a noise model placing more weight on L1 can deliver better results. These options are described in the shaded box.

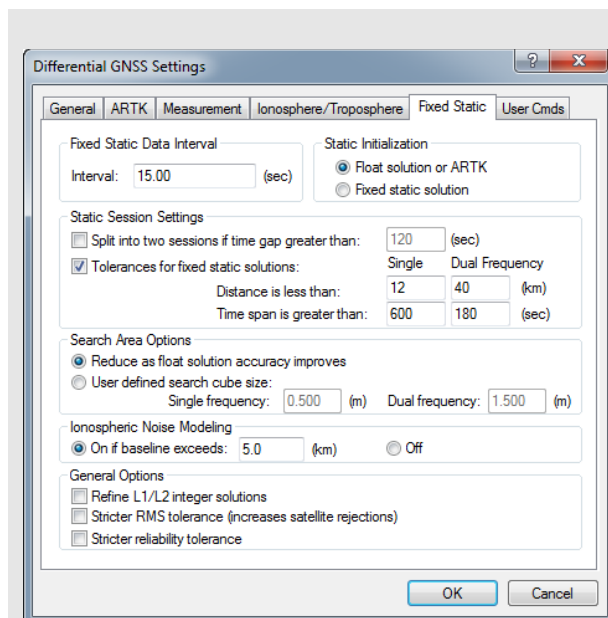
General Options

These options are described in the shaded box.

User Cmds

This changes any command that is passed to GrafNav. It can be used to change commands that are set by the other option tabs, or set commands that are not handled by the other option tabs. See *Appendix C, Summary of Commands* on page 177 for a list of commands.

When a configuration file is loaded, all commands that are not handled by the other option tabs appear here. This includes commands that are not supported in the version of GrafNav being used. These commands can easily be deleted here.



Ionospheric Noise Modeling settings

On if baseline exceeds

Corrects for the ionosphere if the baseline exceeds the specified length.

Off

Use this option to disable the use of L2 for ionosphere corrections.

General Options

Refine L1/L2 integer solutions

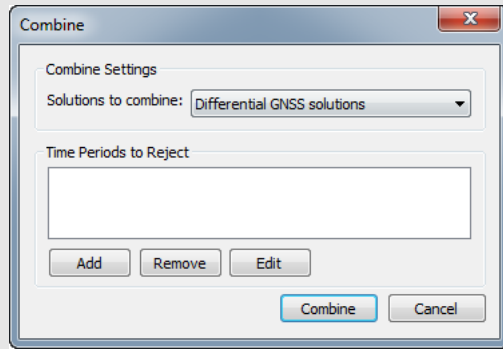
This method uses an alternative ambiguity search algorithm. In general, the standard method used in GrafNav's fixed static processor works best, but this can be a powerful reprocessing option if needed.

Stricter RMS tolerance

If the RMS of the fixed solution is relatively high (cm level) and you believe the solution quality may be suspect (for example, from a large difference in the forward and reverse fixed solutions), this option can be a useful reprocessing option.

Stricter reliability tolerance

If the reliability of the fixed solution is relatively low (below 3) and you believe the solution quality may be suspect (for example, from a large difference in the forward and reverse fixed solutions), this option can be a useful reprocessing option.



2.5.2 Combine Solutions

After processing, forward and reverse solutions are automatically combined. This helps maximize solution accuracy through inverse variance weighting. The combined solution will much more heavily weight each solution when one has a low estimated error (for example, a fixed integer solution) and the other has a relatively high estimated error (such as is the case with a float solution).

Thus, the combined separation should contain the best of both forward and reverse solutions and an average of the results where the estimated errors are approximately equal.

The *Combine* dialog is accessed through *Process | Combine*. Since the forward and reverse solutions are automatically combined in GrafNav, the *Combine* dialog does not need to be used following forward/reverse processing. It should only be used if you have identified specific time ranges from forward or reverse processing that you want to omit from the combined trajectory. An example of this is where an incorrect ambiguity was obtained in one direction, which could not be remedied by changes to the processing options.

This dialog is more frequently used when comparing different modes of processing. For example, a GrafNav project can contain both PPP and differential solutions as each type of solution writes trajectory files with different extensions. This ensures differential and PPP solutions can exist in the same project without overwriting each other.

An easy way of comparing the combined differential and the combined PPP solution within the GrafNav environment is to load and combine both of them into the project at once. This is done by choosing the *Any two solutions* option and then *Combine*. You will be prompted to choose which two solutions to combine. If you choose the .cmb file and the .csp file, you will be combining the differential combined results (.cmb) and the PPP combined result (.csp). After combining, you can plot the difference in the solutions by viewing the *Combined Separation Plot*, which is accessible under *Output | Plot Results*.

However, before exporting ensure that either the differential (.cmb) or the PPP (.csp) solution is loaded, as the Export Wizard accesses whichever solution is presently loaded. One way of re-loading combined results is to choose *Differential GNSS Solutions* or *PPP GNSS Solutions* from this dialog and clicking the *Combine* button.

2.6 Settings Menu

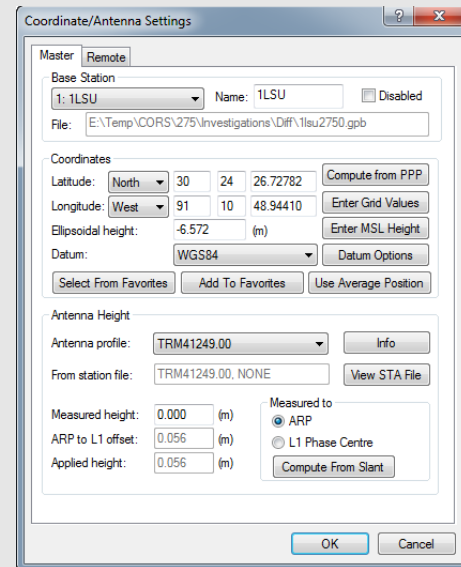
2.6.1 Coordinate/Antenna

Master Station Settings

This option lets you modify the master station coordinates. Coordinates, datum and antenna information can be entered manually or loaded from the *Select From Favourites* button. The *Compute from PPP* button processes the base station data through GrafNav's precise point processor and reports the difference in coordinates between the values on the screen and the computed values. This can be an effective means of checking base station coordinates or in some cases establishing them. See *Section 2.3.6, Add Master File(s)* on page 21 for more information of the settings available.

Remote Settings

This option lets you customize the remote's antenna information. See *Section 2.3.7, Add Remote File* on page 23 for additional information.



The **Coordinate/Antenna Settings** dialog box has two tabs: **Master** and **Remote**. The **Master** tab is active.

Base Station

- Station: 1: 1LSU (dropdown), Name: 1LSU, ☐ Disabled
- File: E:\Temp\CORS\275\Investigations\Diff\1lsu2750.gpb

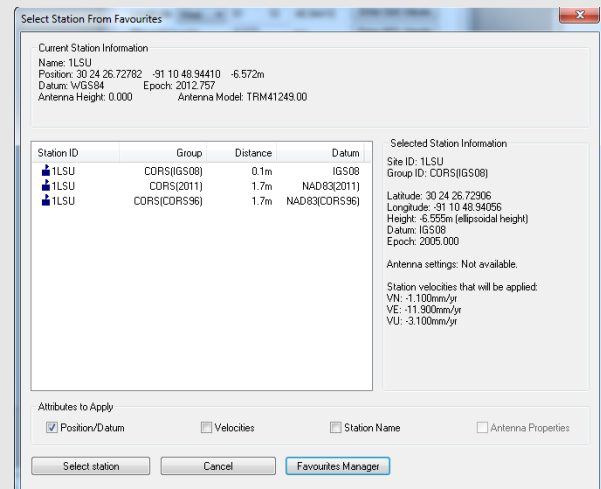
Coordinates

- Latitude: North 30 24 26.72782 (Compute from PPP)
- Longitude: West 91 10 48.94410 (Enter Grid Values)
- Ellipsoidal height: -6.572 (m) (Enter MSL Height)
- Datum: WGS84 (Datum Options)
- Buttons: Select From Favourites, Add To Favourites, Use Average Position

Antenna Height

- Antenna profile: TRM41249.00 (Info)
- From station file: TRM41249.00, NONE (View STA File)
- Measured height: 0.000 (m)
- ARP to L1 offset: 0.056 (m)
- Applied height: 0.056 (m)
- Measured to: ☒ ARP, ☐ L1 Phase Centre (Compute From Slant)

Buttons: OK, Cancel



The **Select Station From Favourites** dialog box shows current station information and a list of available stations.

Current Station Information

- Name: 1LSU
- Position: 30 24 26.72782 -91 10 48.94410 -6.572m
- Datum: WGS84 Epoch: 2012.757
- Antenna Height: 0.000 Antenna Model: TRM41249.00

Station ID	Group	Distance	Datum
1LSU	CORS(IGS08)	0.1m	IGS08
1LSU	CORS(2011)	1.7m	NAD83(2011)
1LSU	CORS(CORS96)	1.7m	NAD83(CORS96)

Selected Station Information

- Site ID: 1LSU
- Group ID: CORS(IGS08)
- Latitude: 30 24 26.72906
- Longitude: -91 10 48.94056
- Height: -6.555m (ellipsoidal height)
- Datum: IGS08
- Epoch: 2005.000
- Antenna settings: Not available.
- Station velocities that will be applied:
 - VN: -1.100mm/yr
 - VE: -11.900mm/yr
 - VU: -3.100mm/yr

Attributes to Apply

- ☒ Position/Datum
- ☐ Velocities
- ☐ Station Name
- ☐ Antenna Properties

Buttons: Select station, Cancel, Favourites Manager

Select From Favourites

Precise coordinates for CORS, IGN and IGS stations are regularly maintained within GrafNav's manufacturer files. If downloading base station data from one of these networks, you can load the published coordinates using the *Select From Favourites* button in the master coordinate dialog. This returns a list of the closest stations to the coordinates loaded.

When selecting a station from favourites, be sure to note the available *Attributes to Apply* at the bottom of this dialog. This provides the ability to copy not only the position and datum information from the favourites, but also the station name, antenna properties (if available) and station velocities. If velocity is selected, the published velocities are applied to the published coordinates to update them to the epoch of data collection.

Azimuth Determination Options

Off, no azimuth determination

Use this option if both antennas are on separate moving platforms and the azimuth between the antennas is not of interest (i.e. only the relative position and/or velocity).

On, use distance constraint in ARTK and engage ARTK if out of tolerance

Use this option if both antennas are fixed to the same moving platform and a post-processed azimuth is required. This option requires that you input the surveyed distance between GNSS antennas as it is used as a distance constraint in ARTK.

On, but compute only (don't use distance constraint at all)

Use this option if the surveyed distance between the antennas is not known, or is known to change significantly during the survey.

On, but only use distance constraint to engage ARTK if out of tolerance.

When this option is used, the distance constraint is not applied when resolving carrier phase ambiguities. Rather, it is used only to re-engage when the computed distance disagrees with the surveyed distance significantly (based on the standard deviation applied to the distance constraint).

2.6.2 Moving Base Options

Enable moving baseline processing if your base station is on a moving platform and you are interested in either a post-processed azimuth between the antennas and/or the local level vector.

Moving base applications may involve both antennas on the same vehicle or separate moving vehicles. Azimuth determination is typically of interest for the former, whereas the local level vector (relative position and velocity) is generally of interest in the latter.

When moving baseline processing is enabled, GrafNav cannot fix the base station position. Every processing epoch uses a different base station position, which is read from the GPB file. The absolute positioning accuracy of each instantaneous base station position is thus limited to the autonomous positioning accuracy of the receiver used. This is generally no better than 2 m horizontal and 5 m vertical.

Although the absolute positioning accuracy in moving base mode is poor, this is not of interest to most moving base applications. Only the relative position difference and/or azimuth between the antennas is typically required. When ARTK resolves carrier phase ambiguities in moving base mode, the relative positioning accuracy between base and remote is the same as in stationary base mode.

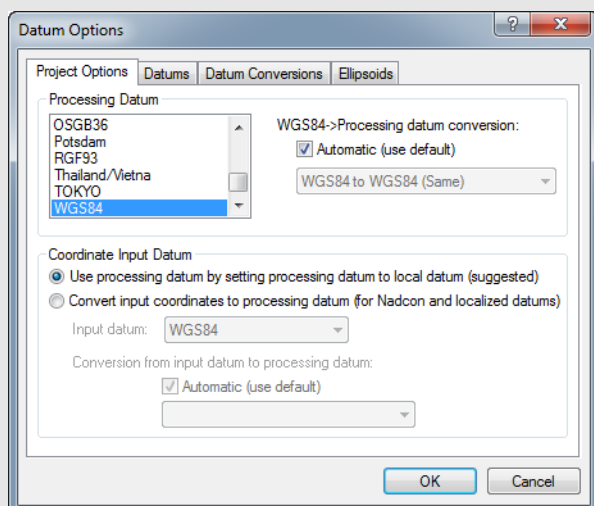
If moving base is enabled, choose from one of the four Azimuth determination options explained in the shaded box.

2.6.3 Datum

Project Options

The processing datum is normally set from the master coordinate dialog when entering base station coordinates. If your base station coordinates are provided in a local datum however, such as NAD27, it is advisable to convert the base station coordinates to a global datum prior to processing, as only global datums should be used as processing datums.

The *Project Options* tab is used to convert input coordinates from one datum to another prior to processing. Note that the processing datum is relatively unimportant provided a global datum is used. This is because a datum transformation can also be applied when exporting results.



Datums

This feature allows custom datums to be added, or existing datums to be enabled or disabled.

Datum Conversions

This tab allows you to view, edit or add conversions between datums.

Ellipsoids

This page allows you to view the a , b or $1/f$ values for a particular ellipsoid. You can also add new ellipsoids.

2.6.4 Grid

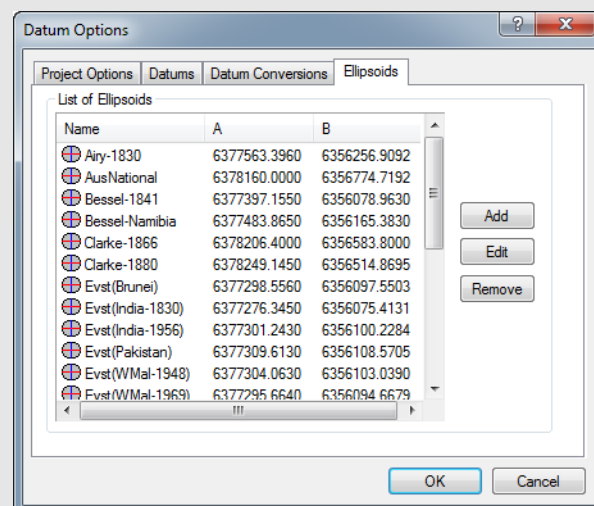
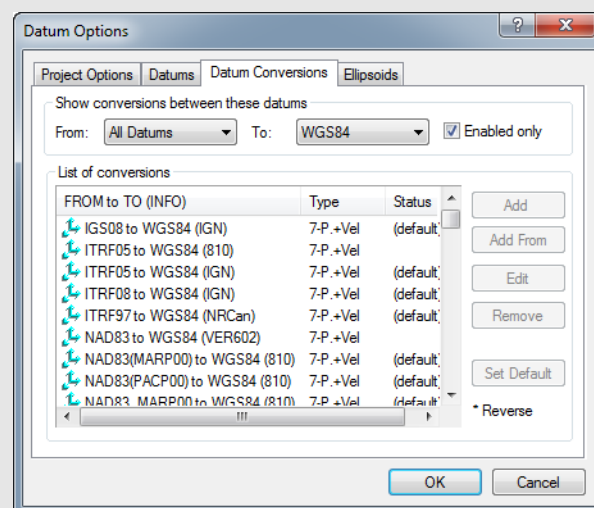
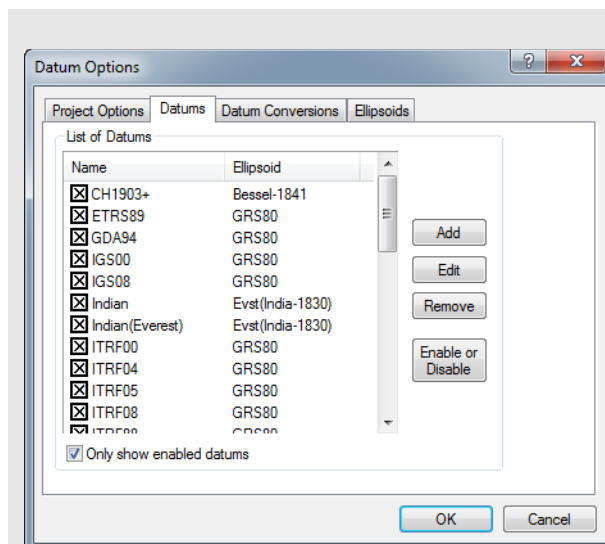
GrafNav supports several international and regional grids, such as UTM, US State Plane, British Grid, Irish Grid etc. Custom grids can also be defined by selecting *Define Grids* within the *Grid Settings for Coordinate Input* dialog.

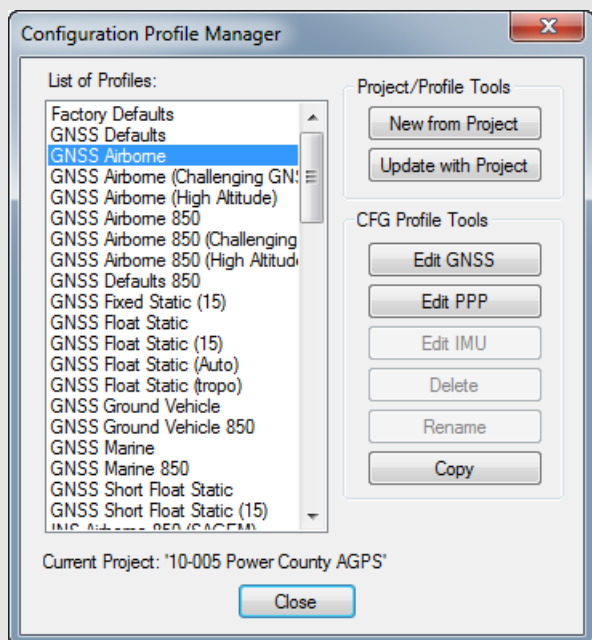
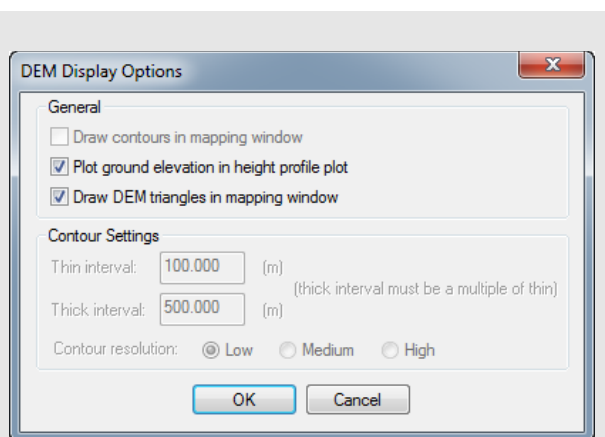
Defining a grid allows the grid to be accessed by the Export Wizard. Base station coordinates can also be added directly in grid format as well.

GrafNav projects store grid information. Set up a grid for the following reasons:

- Master coordinates can be entered directly in a supported grid.
- The *Map Window* can plot in grid coordinates. See *Section 2.7.11, Show Map Window* on page 79 for more details.
- *Export Wizard* can use a defined grid for coordinate output. See *Section 2.7.5, Export Wizard* on page 72 for details.

New grid definitions can be added by clicking *Define Grid* or via *Tools | Grid/Map Projections | Define*. See *Section 2.8.7, Grid/Map Projection* on page 87 for more information.





2.6.5 DEM Plotting

DEM Display Options are available if a DEM has been loaded into the project. See *How to load a DEM* on page 30 for information about loading DEMs.

General

Plotting the ground elevation in the height profile plot

Allows the ground height and the height of processed ellipsoidal height of the remote to be displayed within the *Height Profile* plot.

Drawing the DEM triangles

Displays the TIN model of the network formed. Turning these options off reduces any sluggish response from the program when viewing the *Map Window*.

2.6.6 Manage Profiles

The profile manager allows new profiles to be created or existing profiles to be edited. The profile manager can also be used to edit the GrafNav default settings or restore the factory default settings.

Project/Profile Tools

New from Project

Creates a new CFG profile using the current project's settings.

Update with Project

Updates the processing profile with the current project settings.

CFG Profile Tools

Edit GNSS/PPP/IMU

Brings up the processing settings menu to allow the selected profile to be modified.

Rename

Allows the profile to be renamed.

Delete

Deletes the selected profile.

Copy

Creates a copy of the currently selected profile.

✉ Modifications to pre-loaded profiles are lost if software is re-installed.

2.6.7 Compare Configuration Files

This feature allows you to compare the settings applied in two different configuration files. This utility scans both of the CFG files and creates a report outlining the differences found. This report is displayed in GrafNav's ASCII viewer.

2.6.8 Preferences

Display

This tab allows you to edit what is displayed on the *Map Window*.

General

The following settings are available:

Zoom increment scale factor

This setting affects the size of the displayed symbols and text when zooming. Higher values will result in smaller symbols and text.

Show direction arrows on trajectory

Shows arrows in the direction of travel on the map screen.

Show grid lines in map window

Displays grid lines. Grid lines help show the scale of the project. Depending on user preferences these can be disabled.

Show legend at bottom of map window

Toggles the display of the color-coded quality numbers legend.

Draw White background instead of black

Changes the background color of the Map Window from black to white.

Additionally, the display of all text, epochs, features, ARTK marks, base stations and static sessions can be enabled or disabled from the General tab.

Coordinates for Display

The settings are listed in the shaded box.

Zoom Level Specific

This set of options is based on the *Zoom Level* specified.

Zoom Level

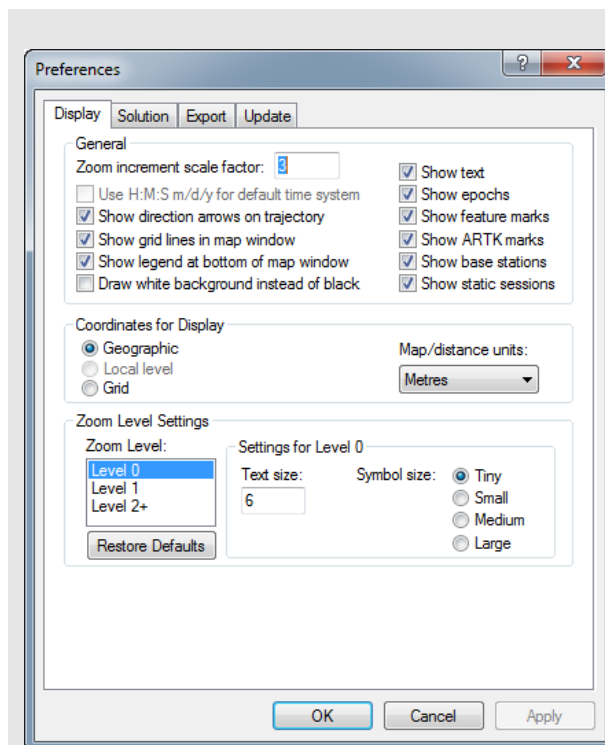
Level 0 is the main screen without being zoomed. Each level has its own set of default display options that can be changed to your preferences.

Text Size

Controls the font size. The *Show Text* option allows text to be seen on the screen.

Symbol Size

Controls the symbol display.



Coordinates for Display

Geographic

Displays the latitude and longitude on the screen. The orientation is such that the positive y-axis is true north.

Local level

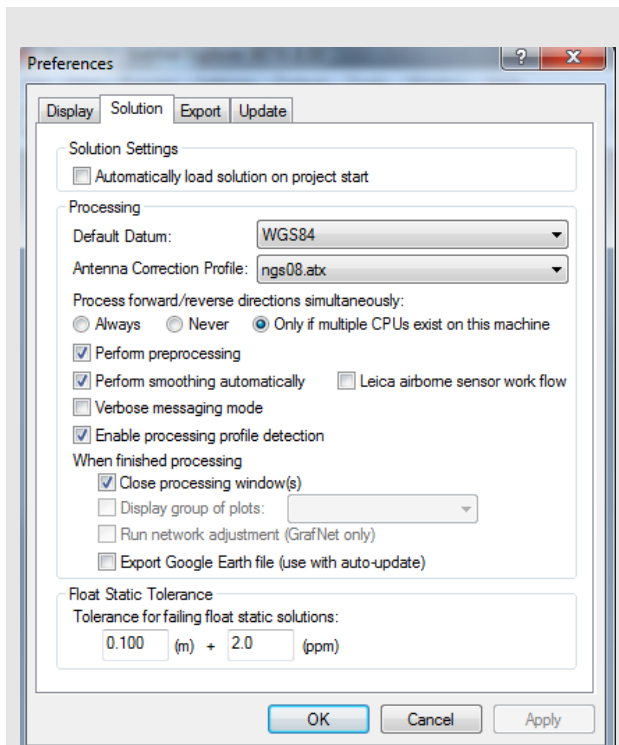
Plots the local level vector if moving baseline processing has been performed. Moving baseline processing should only be engaged if both base and rover are kinematic and the relative vector between them is of interest. Moving baseline processing does not produce accurate absolute positioning results, only accurate relative positioning results.

Grid

Displays the coordinates in the grid selected under *Settings | Grid*.

Map/distance units

Changes the units of the values being displayed for local level or grid coordinates in the *Map Window*. Changes the units displayed when using the *Distance & Azimuth* tool as well. See *Section 2.8.2, Distance & Azimuth Tool* on page 83 for information.



When finished processing

Close processing window(s):

Closes all processing windows after completion.

Display group of plots:

If you have defined a group of plots under *Output | Plot Results*, then you may select it here for automatic display. See *Section 2.7.1, Plot Results* on page 65 for help creating a group of plots.

Export Google Earth file:

The software writes a KML/KMZ file to the *HTML* folder, which is located in the project folder. If the *Output | Export to Google Earth | Create Auto-Update Entry* option has been used, then Google Earth updates the new trajectory.

Solution

Solution Settings

Automatically load solution on project start

Loads the combined trajectory when re-opening a project that has been previously processed.

Processing

Default Datum

Allows you to select a default processing datum for all GrafNav projects. This datum automatically appears when adding base station data in the *Master Coordinate* dialog, as well as within the *Process GNSS* dialog.

Antenna Correction Profile

GrafNav 8.50 supports absolute antenna models. Absolute calibrations are provided by organizations such as the NGS (National Geodetic Survey) and IGS (International GNSS Service) in ANTEX format.

GrafNav installs ngs08.atx (provided by the NGS) to the *manufacturer* directory. See the *Update* tab within *Settings | Preferences* to locate this directory if needed. Absolute calibration files are regularly updated by the organizations that provide them, and thus Waypoint includes the latest version in regular updates to all of GrafNav's *manufacturer* files. Provided an internet connection, GrafNav will check the NovAtel server on a bi-weekly basis to ensure these files stay up to date.

Although GrafNav will only include, and will only maintain, ngs08.atx, a user can download any ANTEX files (such as IGS08.atx or IGS05.atx) required and add them manually to the *manufacturer* directory. Any file with a *.atx extension is available for selection from this pull-down menu and if selected will become the source of absolute antenna models.

Process forward/reverse directions simultaneously

This feature improves processing speed considerably for computers with dual core or Xeon processors.

Perform smoothing automatically

This feature is disabled in GrafNav as it is applicable only to Inertial Explorer.

Verbose messaging mode

Enabling this option will result in all processing messages being written to the processing windows. If disabled, only high priority messages, such as those concerning measurement errors and ARTK fixes will be displayed. It should be noted that all messages will be written to the Message Log files regardless of this setting.

Enable processing profile detection

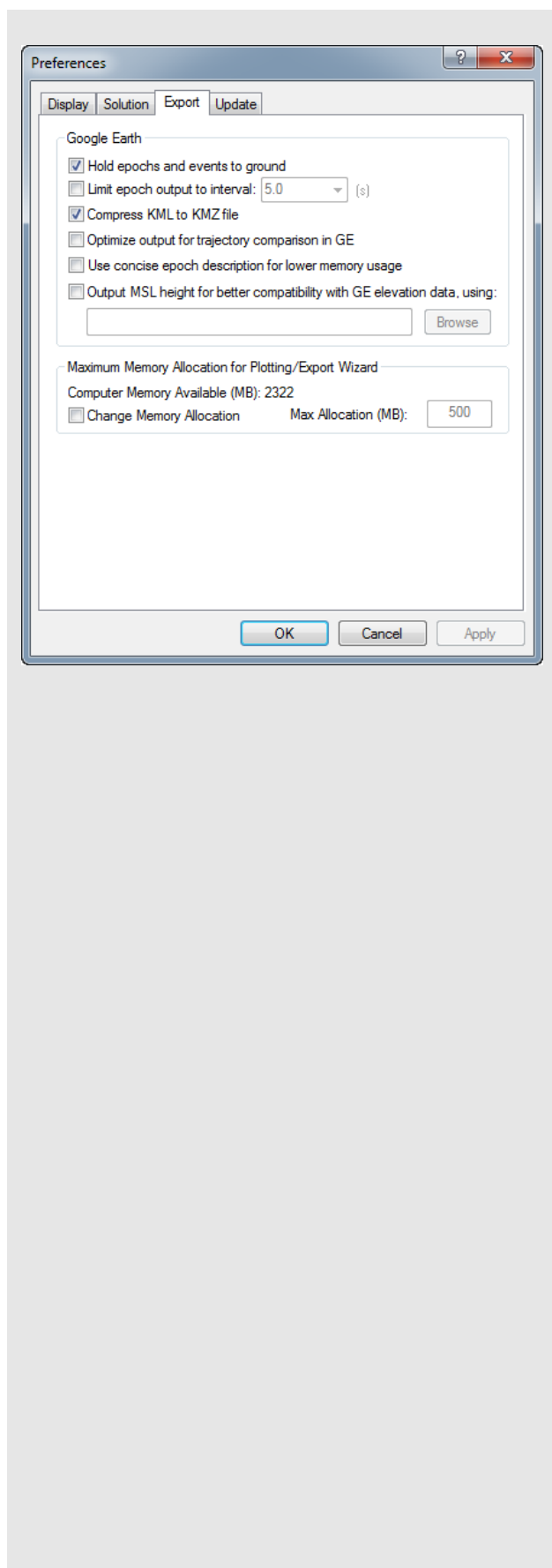
During the conversion of raw GNSS data to GPB, you have the option of having pre-processing checks performed. One of these checks includes trying to determine what type of application/environment the data was collected in. When this option is enabled, the software will use this information to automatically select the best processing profile. The profile can be overridden regardless of this setting.

Leica airborne sensor work flow

This option enables the Leica IPASS workflow within Inertial Explorer and is intended for customers who have purchased Inertial Explorer directly through Leica. Engaging this option affects the folder structure created during decoding and processing and will auto-generate a *.sol file after processing.

Float Static Tolerance

Allows you to adjust the pass/fail settings for float static solutions. These options can be adjusted for specific applications where high accuracies are not required or expected, such as when collecting static sessions in challenging GNSS signal environments.



Export

Hold epochs and events to ground

This option plots the trajectory on the ground in Google Earth. This option is recommended for ground surveys.

Limit epoch output to interval

You can reduce the density of the output trajectory by specifying an interval here. This helps reduce file size and loading times in Google Earth.

Compress KML to KMZ file

Due to their ASCII nature, KML files can be quite large. The KMZ format allows for a much smaller file without losing any information.

Optimize output for trajectory comparison in GE

By default, the software overwrites the same project KML/KMZ file, while using the Quality Number to determine the color of the epochs used for display purposes. However, if you wish to compare multiple solutions for the same trajectory, enable this option to ensure that a new output file is written. To make it easier to distinguish between each solution in Google Earth, each new output file is assigned its own specific color. That is, the Quality Number is ignored. In addition, a new folder is created if the *Run* descriptor has changed.

Use concise epoch description for lower memory usage

The default output files written by the software contain a lot of additional information, which can really slow down Google Earth. If this information is not needed in the output file, a more concise output file can be written.

Output MSL height for better compatibility with GE elevation data, using

Google Earth expects orthometric (mean-sea-level, MSL) height values. As such, if *Hold epochs and events to ground* is disabled, the plotted height may be below ground level (if the geoid undulation is negative) and the object is at ground level. Use the *Browse* button to locate the Waypoint Geoid (WPG) file. Other geoid formats are not supported. The EGM96 geoid, which covers the entire world, has sufficient accuracy for this purpose.

Maximum Memory Allocation for Plotting/Export Wizard

Change Memory Allocation

The software allocates memory up to the specified maximum based on the number of epochs in the project. This value is dependent on the length of the data collection as well as the data rate. If the software cannot allocate enough memory to accommodate the entire trajectory, it pages to disk when plotting or exporting and may degrade performance. Do not lower this value unless your computer lacks memory.

2.7 Output Menu

2.7.1 Plot Results

GrafNav provides access to over 40 plots that are helpful in quality control. When expanding the main *Plots* branch, you will see that the plots are sorted within sub-groups, such as *Accuracy*, *Measurement*, *Coordinate Values* and others. The *Most Common* group will appear empty immediately after you install the program for the first time, but over time will be populated with up to 10 of your most commonly accessed plots. To see all of GrafNav's plots, expand the *All* group.

Within each group, plots appear as one of three colors: green, blue or black. The green plots always appear above the blue plots, and the blue plots always appear above the black plots.

The color coding scheme is similar to a ski hill, where green plots indicate beginner, blue plots indicate intermediate, and black plots indicate advanced. These three main categories do not indicate the type of user that should access these plots. They indicate that the green/beginner plots are more frequently accessed than the blue/intermediate and so on. Therefore beginner and advanced users will more frequently access the green plots than any other.

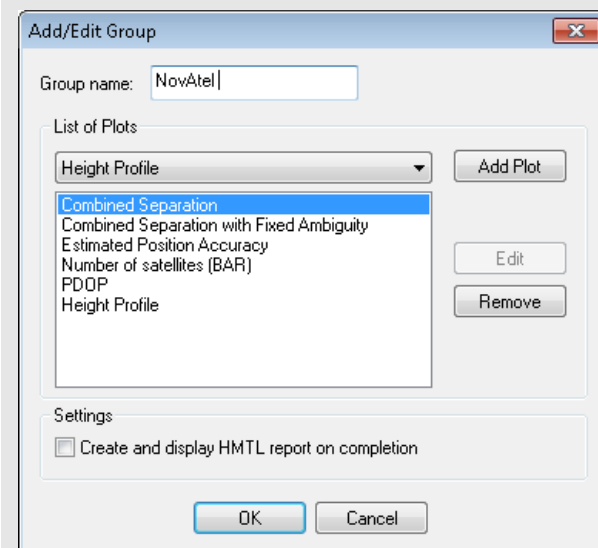
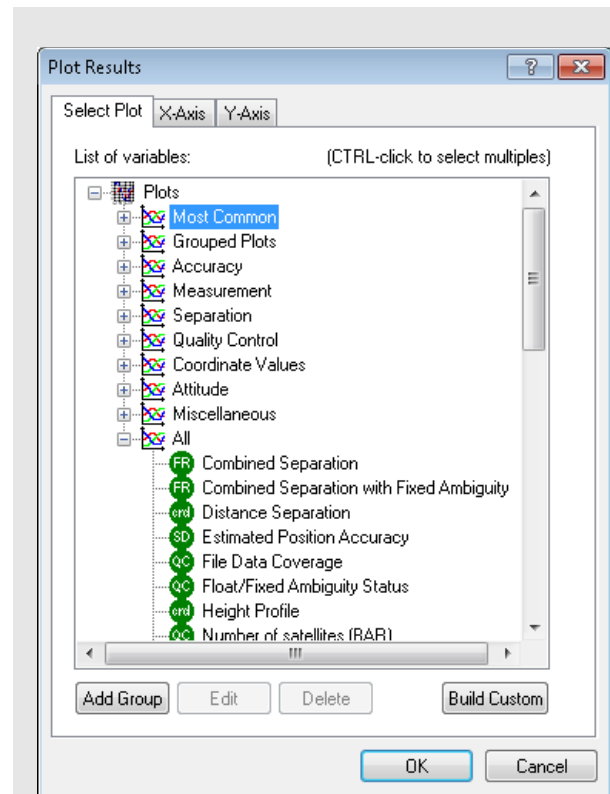
Many plots support different units. For example, you can plot the *Combined Separation*, which shows the difference between forward and reverse solutions in meters or feet. The *Distance Separation*, or baseline distance, can be plotted in units of kilometers, miles or meters. In order to change units on a plot, first select the plot from the list and then access the *Y axis* tab. This tab has a *units* pull down list which shows supported units for the selected plot. After changing units, your preference is remembered for all projects.

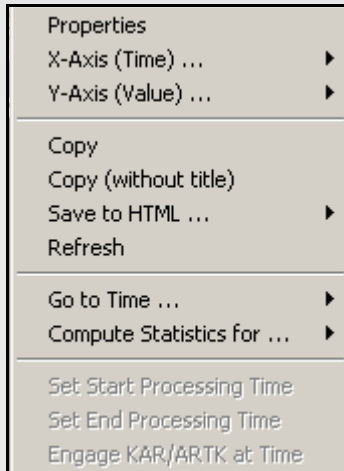
Individual plots can be viewed by double clicking a plot in the list, or by selecting the *OK* button after selecting a plot. Multiple plots can be accessed simultaneously by using the *Ctrl* key prior to selecting the *OK* button. Further, if a plot group of plots has been created using the *Add Group* button, all plots within the group are plotted simultaneously.

Add Group

You may wish to add a group of plots for the purpose of plotting the entire group simultaneously. For example, if after processing you always want to see the *Combined Separation*, *Number of Satellites (BAR)*, *PDOP* and *Estimated Position Accuracy*, these four plots can be added to a custom group.

When you click the *Add Group* button, a second dialog appears that allows you to provide the group a name and add plots to your group. There is also an option for launching an HTML report that includes the grouped plots and the Map Window.



**X -Axis (Time)...****Select X-Range**

Previously used settings of the X-axis are stored here.

Apply to All

Scales the X axis of the other opened plots to facilitate analysis.

Auto-scale

Shows the entire time range of the data.

Set Minimum

Makes the current time the X-axis minimum.

Set Maximum

Makes the current time the X-axis maximum.

Y-Axis (Value)...**Select Y-Range**

Previously used settings of the Y-axis are stored here.

Apply to All

Scales the Y axis of the other opened plots to facilitate analysis.

- ☒ In order to apply the Y axis to all plots, the maximum and minimum values must be manually specified, that is, not auto-scaled.

Auto-scale

Shows the entire value range of the data.

Set Minimum

Makes the current time the X-axis minimum.

Set Maximum

Makes the current value the Y-axis maximum.

Build Custom

This option allows plots to be added to the *Custom* group. Adding the plots you most commonly access here makes them more accessible than choosing them out of other groups, or from the *All* list.

The difference between creating a *Grouped plot* and adding plots to the *Custom* group is that grouped plots will all be plotted simultaneously, whereas plots to the *Custom* list can still be accessed individually.

Plot Options

When you right click on a plot, a menu of options appears.

Properties

Allows access to many settings, like X and Y axes ranges and the display format for the latter. The plot titles, along with the X and Y axes labels, can be edited here. Other options regarding the displaying of camera marks and the usage of thick plotting lines are available too.

X -Axis (Time)...

The options are described in the shaded box.

Y-Axis (Value)...

The options are described in the shaded box.

Copy

Copies the plot to the clipboard as a bitmap (BMP), allowing you to paste the image into other application such as Microsoft Word or Paint.

Copy (without title)

Copies the plot to the clipboard as a bitmap (BMP) without the plot title.

Save to HTML

Copies a BMP version of the plot into an HTML file, which opens upon completion. The HTML and BMP files are saved to the project folder under a directory called *HTML*.

Refresh

Reloads the selected plot.

Go to Time...

Gives you the option of finding the nearest available time in the forward or reverse message logs, or finding the nearest epoch on the *Map Window*.

Compute Statistics for...

Calculates many useful statistics for either the entire valid processed time range, or, if it has been adjusted, only the time range being plotted. Statistics include RMS, average, maximum and minimum. Note that this feature is only available for appropriate plots.

Set Start Processing Time

Makes the selected time the start time for processing.

Set End Processing Time

Makes the selected time the end time for processing.

Engage ARTK at Time

Engages ARTK at the selected time.

2.7.2 Common Plots

Table 1, *Common Plots* contains a list of common plots that are available through the *Plot GPS* window.

Table 1: Common Plots

Plot	Description
Accuracy	
Estimated Position Accuracy	Plots the standard deviations of the east, north and up directions versus time for the solution. The total standard deviation with a distance dependent component is also plotted. View this plot for individual forward or reverse solutions and losses of lock.
Measurement	
RMS – C/A Code	Plots the RMS of the double differenced C/A residuals for all satellites used in the solution. Under good conditions, this indicates C/A measurement accuracy. High C/A residuals often indicate high multipath. Also plotted is the standard deviation applied to the C/A measurements within the Kalman Filter. This value comes in part by the a-priori value set in the <i>Measurement</i> tab. In dual frequency carrier phase processing, where ARTK is used to resolve integer carrier phase ambiguities, the C/A code does not heavily influence solution accuracy. Thus the standard deviation assigned to the measurements is not important, provided it is not overly optimistic. Adjusting the C/A measurement standard to a value more representative of the size of the actual residuals (while still being conservative) will benefit float solution convergence.
RMS – Carrier Phase	Plots the RMS of the double differenced carrier phase residuals for all satellites used in the solution. Under good conditions and with a short baseline, it is a good indication of carrier phase measurement accuracy. Carrier phase noise increases as the baseline length grows due to factors such as residual ionospheric error. Further, if ionospheric processing is used, the carrier phase noise will increase noticeably (although it should still be cm level). Thus, while values at or below 1 cm may be typical for short baselines (1-2 km), values of 2-4 cm are typical for longer baselines (10-40+ km). If large differences are found in the <i>Combined Separation (fixed)</i> plot, the RMS of the carrier phase can be a very helpful plot in determining which direction (forward or reverse) the incorrect ambiguity occurred. When doing this, ensure to load each solution (forward and reverse) separately prior to plotting the carrier phase RMS, in order to ensure you are viewing the carrier phase residuals for each direction separately. Large ramping trends are strong indications of incorrect ambiguities.
(Sheet 1 of 4)	

Table 1: Common Plots (continued)

Plot	Description
RMS-L1 Doppler	<p>Plots the RMS of the double differenced Doppler residuals for all satellites in the solution. GrafNav uses Doppler to compute instantaneous velocity. Also plotted is the measurement weighting applied to the Doppler measurements within the GrafNav Kalman filter. As the quality of the Doppler measurements varies very significantly between receiver manufacturers, GrafNav applies a conservative default measurement weight. Therefore it is common to see that the actual Doppler residuals are much lower (better) than the weight applied in our filter. This will only cause the estimated velocity errors to be much higher than the actual velocity accuracy. Some receivers output such noisy Doppler values (on the order of 5 m/s) that it will actually cause Kalman Filter resets, significantly degrading positioning accuracy. Thus if you see very large residuals in this plot, we recommend disabling Doppler from the <i>Measurement</i> tab of the GNSS processing options. When doing this, velocity is not derived from Doppler but rather through a carrier phase model.</p>
Satellite Lock – Cycle Slips	<p>This plot launches a dialog that provides access to the L1 and L2 cycle slip plots for all GPB files within the project, or a user defined GPB file. Each satellite in the GPB file is plotted as a function of time and is color coded by elevation. See the bottom of the plot for a legend. Cycle slips for individual satellites are represented as a vertical red tick mark on the plot. It is normal for cycle slips to occur on low elevation satellites (< 10 degrees) due to signal blockages or due to attenuation by the GNSS antenna. Cycle slips on high elevation satellites may be expected if surveying in a challenging GNSS signal environment and are thus not necessarily an indication of a problem. However, if the plot shows many cycle slips on L1 or L2 in aerial survey applications where good signal tracking is expected, it can help diagnose receiver or antenna problems that can significantly limit post-processing performance. If you are getting poorer than expected post-processing performance, checking the quality of L1 and L2 signal tracking at the remote and base stations is a good first step in determining the cause.</p>
Individual Satellite Statistics	Shows satellite code residuals, phase residuals, elevation angles and C/NO values for individual PRNs.
(Sheet 2 of 4)	

Table 1: Common Plots (continued)

Plot	Description
Separation	
Combined Separation	<p>Plots the north, east and height position difference between any two solutions loaded into the project. This is most often the forward and reverse processing results, unless other solutions have been loaded from the <i>Combine Solutions</i> dialog.</p> <p>Plotting the difference between forward and reverse solutions can be very helpful in quality checking. When processing both directions, no information is shared between forward and reverse processing. Thus both directions are processed independently of each other. When forward and reverse solutions agree closely, it helps provide confidence in the solution. To a lesser extent, this plot can also help gauge solution accuracy.</p> <p>Large differences in the combined separation plot may be a result of different levels of solution convergence and thus not indications of problems. Thus it is important to also consider solution status (fixed/float) when evaluating forward/reverse differences. This is why the <i>Combined Separation with Fixed Ambiguity</i> plot can sometimes be more helpful.</p>
Combined Separation with Fixed Ambiguity	<p>Similar to the <i>Combined Separation</i> plot, however only the position differences between forward and reverse processing are plotted where both solutions have fixed integer ambiguities. Fixed integer solutions are associated with high accuracies (cm, or cm-level accuracies depending on other factors). Knowing this, there is an expectation of cm level differences between forward and reverse fixed integer solutions. If large differences (decimeter or meter level) are obtained, an incorrect ambiguity was very likely obtained in one or both directions.</p> <p>In this event, loading each solution into the project individually and plotting the <i>RMS - Carrier Phase</i> can be useful in determining in which processing direction the problem occurred. See the description for the <i>RMS - Carrier Phase</i> plot for more information.</p>
Quality Control	
PDOP	<p>PDOP is a unit less number which indicates how favorable the satellite geometry is to 3D positioning accuracy. A strong satellite geometry, where the PDOP is low, occurs when satellites are well distributed in each direction (north, south, east and west) as well as directly overhead. Values in the range of 1-2 indicate very good satellite geometry, 2-3 are adequate in the sense that they do not generally, by themselves, limit positioning accuracy. Values between 3-4 are considered marginal, and values approaching or exceeding 5 can be considered poor.</p> <p>If PDOP is very poor in your survey, try reprocessing with a lower elevation mask (however care should be taken when lowering this value below 10 degrees).</p>
(Sheet 3 of 4)	

Table 1: Common Plots (continued)

Plot	Description
Float/Fixed Ambiguity Status	This plot indicates, on an epoch-by-epoch basis, whether a fixed solution was achieved or if only a float solution is available. If both forward and reverse solutions achieved a fix, the plot shows a value of 2. If either the forward or reverse achieved a fix, but not both, a value of 1 is plotted. If neither direction achieved a fix, a value of 0 is plotted. This plot can be helpful to view in conjunction with the <i>Combined Separation</i> plot, as it will help determine if large values in the forward/ reverse separation are expected or not, depending on solution status in each direction.
Number of Satellites (BAR)	Plots the number of satellites used in the solution as a function of time. The bar plot displays the total number of satellites (GPS and GLONASS if present). It does not distinguish between how many satellites are tracked from each constellation.
Number of Satellites (LINE)	Plots the number of satellites used in the solution as a function of time. The number of GPS satellites, GLONASS satellites and the total number of satellites are distinguished with separate lines.
File Data Coverage	Plots the coverage of each GPB file in the project, or a user specified GPB file, as a function of time. This plot indicates whether the data has been converted as static or kinematic (by different color codes) and shows the presence of any detected complete losses of carrier phase lock by vertical bars. This plot is useful in determining whether any base station data does not overlap with the time range collected by the remote receiver.
Coordinate Values	
Distance Separation	This plot shows the distance between the master and remote. For multi-base distance separation, see <i>Section 2.7.3, Plot Multi-Base</i> on page 71.
Height Profile	Plots the ellipsoidal height of the remote as a function of time.
Velocity Profile	Plots the north, east and up velocity. Also plots the horizontal speed.
(Sheet 4 of 4)	

2.7.3 Plot Multi-Base

Multi-base plots are available if more than one base station has been added to your GrafNav project. In this case, the multi-base plots are often more helpful than the main plots, as they distinguish results from each baseline.

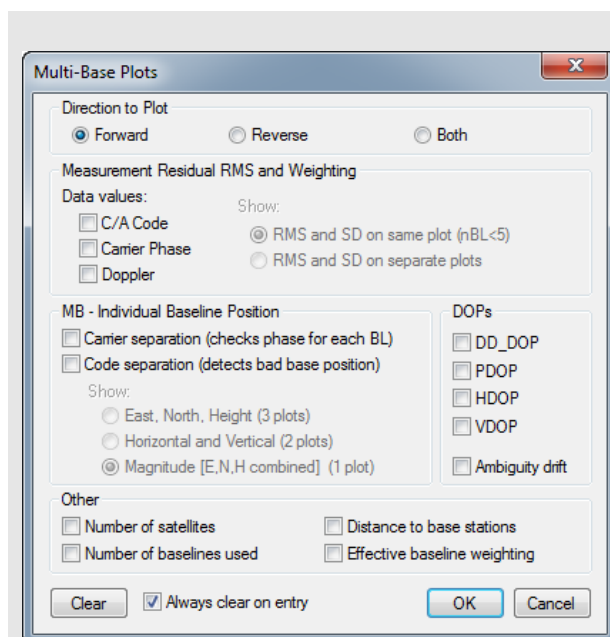
The multi-base plots contain many of the same plots as the main plotting options and therefore only the plots unique to multi-base are described in the following table.

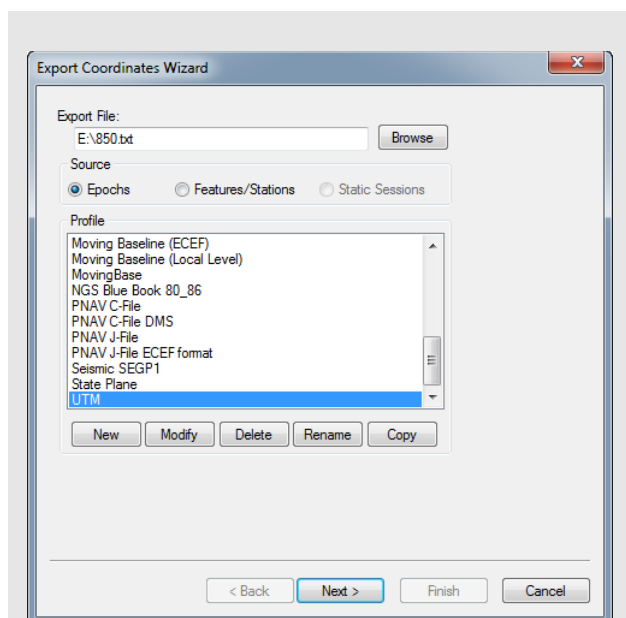
Table 2: Common Multi-base Plots

Plot	Description
Separation	
Carrier Separation	One common reason for poor multi-base results is biased base station coordinates from one or more base stations. This plot is helpful in determining which base station is the outlier, if only one exists. <i>Carrier Separation</i> plots the difference between the multi-base position as processed using data from all base stations and a least-squares based solution using the carrier ambiguities for each base station. If the measurements from one base station are affected by a bias, such as due to incorrect base station coordinates, it should be clearly shown in this plot.
Code Separation	Similar to <i>Carrier Separation</i> , however the position computed in the least squared solution, which is compared against the processed multi-base solution, is derived on code measurements only (not solved carrier phase ambiguities). Thus, this plot attempts to show the same thing as the carrier separation, but is often less helpful due to the accuracy difference between code and carrier measurements.
Effective Baseline Weighting	Plots the relative weighting applied to each baseline. This is largely dependent on the distance to each base station.
Quality Control	
Number of Baselines	Shows the number of base stations used as a function of time.

2.7.4 Plot Master / Remote Satellite Lock

This option displays both the L1 and L2 *Satellite Lock – Cycle Slips* plot for all the master and remote files in the project. See *Table 1, Common Plots* on page 67 for more information regarding this plot.





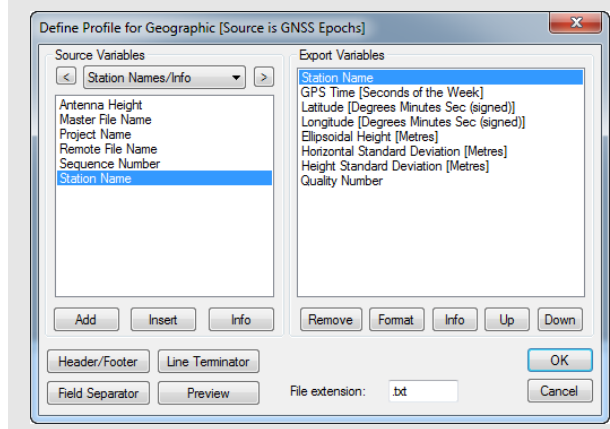
How to create a new Export Wizard profile

1. Click the *New* button and type in a unique name for the profile.
Alternatively, it may be quicker to modify a copy of an existing profile that contains most of the variables required.

2. In the *Define Profile* window, add the desired variables from the *Source Variables* list. All source variables are organized under various headings from a pull down list.

After selecting a variable, click *Add* to add the variable to the bottom of list or *Insert* to add the variable above the highlighted variable in the list. See *Table 3, List of Output Variables* on page 171 for a list of variables available for output.

3. After you are finished adding all the necessary components of the profile, click the *OK* button to save the profile.



2.7.5 Export Wizard

GrafNav's Export Wizard facilitates customized ASCII exporting of processed results. Several manufacturer profiles are included with the installation, however they can be edited and new profiles can be created.

When creating or editing an export profile, you can choose from over 150 source variables. Units, precision, column width, field separators, and header/footer information can all be customized.

You can choose to export all processed epochs, interpolated results for features/stations (such as camera marks) or static sessions. GrafNav will try to auto-detect which *Source* to use given the data in your project. For example, if more than 80% of the remote file is static, the *Source* will default to *Static Sessions*. If more than a handful of features are loaded into the project, the *Source* will default to *Features/Stations* as this is presumably the data of interest.

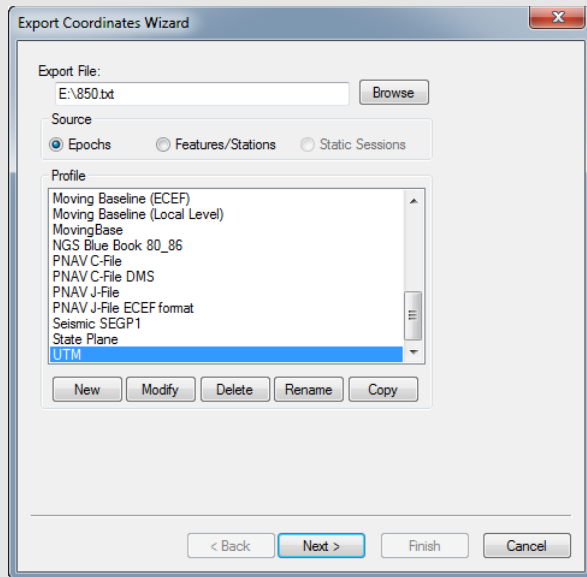
Tips for creating an export profile

- To create a profile that does not have spaces between variable entries and the record based on column width, follow these steps:
 1. Go to the *Define Profile* window.
 2. Click the *Field Separator* button.
 3. Select *None* under *Separation Character* to remove any field separators in the file.

☒ The same procedure can be used to have the output be space or comma delimited.

- To change the file by adding a header/footer of a specific format, the *Header/Footer* button in the *Define Profile* window allows you to add headers/footers from a predefined text file. If specific characters are needed to designate the start and end of a text file, strings of characters can also be added to the beginning and end of the file.
- For formats that require no decimal points to be shown in the file, like SEGP1 and Blue Book, the decimal points can be removed by going into the chosen variable, clicking the *Format* button in the *Define Profile* window, and enabling the *Do not print decimal point* option.
- If you need a text string label to designate the type of record being printed/read that is, \$--GLL, *81*, open up the *Miscellaneous* variable category and add user *Text String* variable. Change the format of the string by entering the text needed for the label and select the *Fixed Width* option if the format is dependent on column width.
- Review the *Header/Footer* button. You can put in your own header file and display datum/projections information, column descriptions and titles. A special character can also be inserted at the start of each header line making it easier for other software to skip past the header. At the bottom of the file, you can add errors/warnings of any problems that were encountered and processing summary information.

☒ Table 3, *List of Output Variables* on page 171 describes the many variables that you can include your output profiles. Not all variables are available for use with each source.



How to use the Export Wizard

1. By default, the export file name is the same name and directory as the project file (.cfg), except with a .txt extension. The file name and directory of the export file can be changed using the *Browse* button.
2. Ensure the *Source* has been set correctly according to what you would like to export.

Choosing *Epochs* produces an output record for each common measurement epoch for the entire trajectory.

Choosing *Features/Sessions* exports results, linearly interpolated between the nearest two epochs, for any camera marks, features or stations loaded.

Static Sessions is accessible provided static sessions have been collected. Choosing this option exports the final post-processed (best converged) solution for each static session.

3. Choose an export profile and select *Next* to start the Wizard. Depending on the variables in the profile, the Wizard will prompt you for any needed information. For example, if the chosen export wizard profile contains orthometric heights, you will be prompted to locate a Waypoint geoid file (.wpg).
4. Click *Finish* on the last page of the Wizard. If *View ASCII output file on completion* was selected on the last page of the Wizard, the text file will open within GrafNav's internal ASCII viewer.

Creating an Output File

The following is an example of the Export Wizard dialogs that appear when exporting *Epochs* using the *Geographic* profile.

Note that when exporting *Features* or *Static Sessions*, or when choosing a different export profile, you may see different dialogs. This is because the Wizard only prompts you for the required information according to your selections.

Select Output Coordinate Datum

The first page of the Wizard provides an opportunity to apply a datum transformation during export. This is required if the datum you wish to export to is not the same as the processing datum.

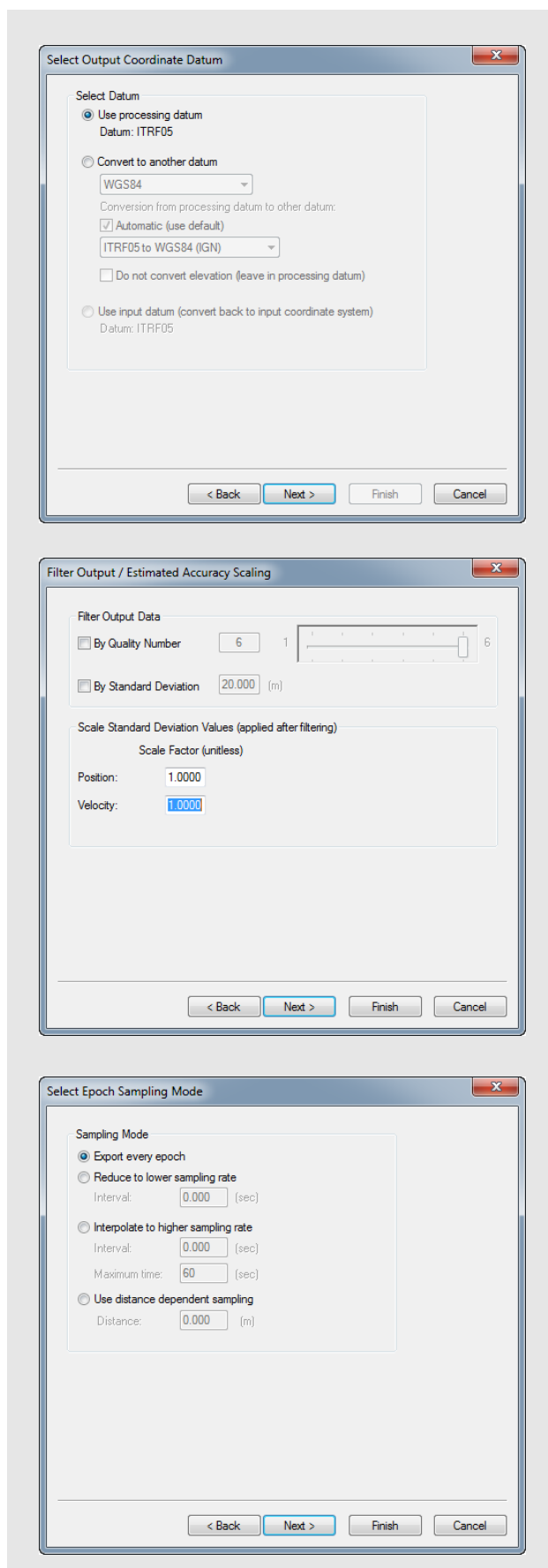
Filter Output/Estimated Accuracy Scaling

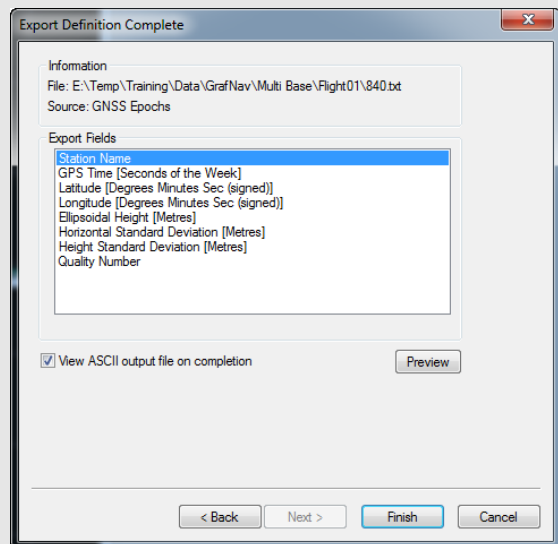
Results can be filtered using either GrafNav's quality numbers or combined (3D) standard deviation. An example of when it is useful to filter by quality number is when only fixed integer solutions are to be exported. In that case, apply a value of 1 for the quality number filter.

This dialog also provides an opportunity to scale the standard deviations output by GrafNav to a higher confidence interval. By default GrafNav outputs 1-sigma values. However due to the conservative measurement weighting applied in GrafNav to code, carrier, and Doppler measurements, they are not by nature overly optimistic.

Select Epoch Sampling Mode

When exporting epochs, you can choose to export all processed epochs, reduce to a lower sampling rate, interpolate to a higher sampling rate, or even apply distance dependent sampling, if results are required at regular intervals.





Export to Google Earth Options

Export and View

Writes a KML/KMZ file to the HTML sub-directory and automatically opens it in Google Earth.

Export Only

Writes a KML/KMZ file to disk, but does not launch Google Earth.

Create Auto-Update Entry

Creates a network link within Google Earth which scans the project KML/KMZ file every 15 seconds for changes. This option can be used along with the *Export Google Earth file* option under *Settings | Preferences* to completely automate the writing and loading of KML/KMZ files. See *Export* on page 64 for more information.

For additional customizing of the Google Earth output files produced by the software, see *Export* on page 64.

Export Definition Complete

The last page of the Wizard provides a summary of the file name and path where the file will be written and the *Source* to be exported. The export variables within the profile are also summarized. Optionally, the output file can be viewed after export by selecting *View ASCII output file on completion*.

2.7.6 View Coordinates

This opens the last file generated by the Export Wizard in GrafNav's internal ASCII viewer.

2.7.7 Build HTML Report

Creates an HTML file containing a bitmap version of any plot that is currently open, including the Map Window. These HTML and BMP files are saved to the *HTML* folder contained within the project folder. The HTML file also contains information regarding the processing run(s) used to generate the plots.

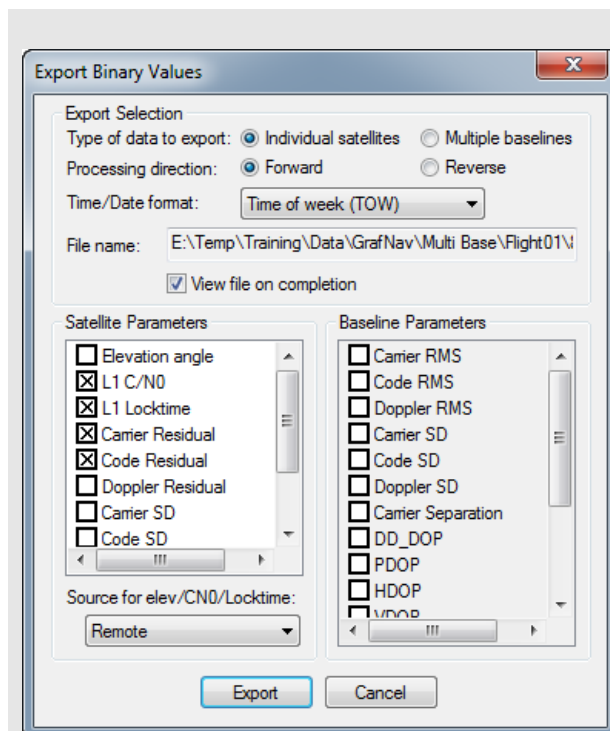
2.7.8 Export to Google Earth

These options are listed in the shaded box.

2.7.9 Export Binary Values

When processing, GrafNav automatically writes a forward (.fbv) and reverse (.rbv) binary file which contains individual satellite statistics and other information. This data is not of interest to commercial users, but may be of interest in research or applications that involve specialized testing.

This option allows the contents of this file to be extracted from the binary file to text. It also provides the ability to extract data found in GPB files, such as the satellite elevation, signal to noise ratio and locktimes. More information about the type of data that can be exported using this utility is in the shaded box.



Export Selection options

Type of data to export:

Select whether values for each satellite should be exported or for each baseline (MB processing only).

Processing direction:

For processing values, forward or reverse values can be exported. For values found in the GPB files, such as satellite elevation, C/N0 and locktimes, the direction is unimportant.

Time/Date format:

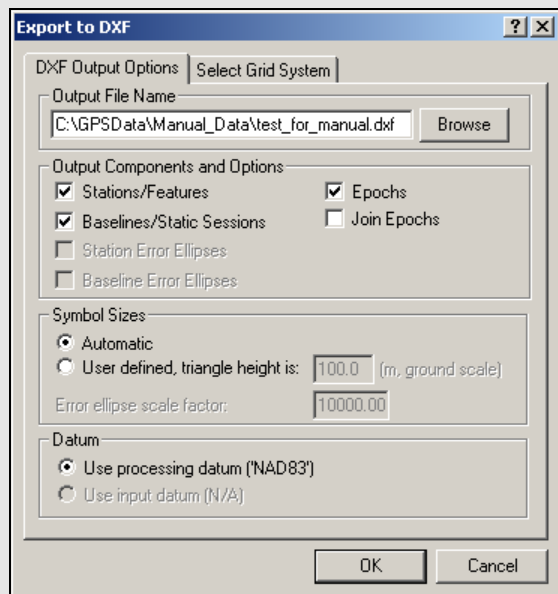
A number of time outputs are possible. See *Section 2.7.5, Export Wizard* on page 72 for more information on each format

File name:

Displays the name of the file.

For GPB based values like *L1 C/N0* and *L1 Locktime*, select whether to export the data from the base or rover files.

See *Section 2.7.5, Export Wizard* on page 72 for a description of the available individual export values.



2.7.10 Export DXF

DXF is a file format read by various CAD packages. This utility outputs the contents of the map window to DXF format.

Output File Name

Specify the name and path of the DXF to be created.

Output Components and Options

The following options are available:

Stations/Features

Outputs any stations or features loaded.

Baselines/Static Sessions

Outputs baselines between all the static sessions. The color of the baselines will be the same as it appears in GrafNav and is determined by the quality factor.

Epochs

Outputs the trajectory and is only useful for kinematic data. Color is determined by the quality factor.

Join Epochs

Joins a line between epochs.

Symbol Sizes

These settings govern the size of the features and stations in the DXF file. *Automatic* is suggested for a trial.

Datum

Allows you to choose between the processing datum or the input datum.

The grid options are available under the *Select Grid System* tab. For UTM, State Plane or any other zone-dependent grid, check that the zone number is correct because the default is likely wrong.

2.7.11 Show Map Window

Prior to processing, the Map window displays the unprocessed positions within the remote GPB file. These positions usually reflect the real time position as logged by the remote receiver.

After processing, the Map window displays the processed results, color coded by quality number. Quality numbers, which range from 1-6, are meant to convey only a general indication of solution quality. A description and the approximate accuracies associated with each quality number is provided in *Table 3, Quality Number Description*. GrafNav's Q/C plots should be accessed for a more detailed analysis of solution quality. See *Section 2.7.2, Common Plots* on page 67 for descriptions of commonly accessed plots.

The information displayed to the Map window is fully customizable from the *Display* tab within *Settings | Preferences*. Users can choose whether to display text, epochs, feature marks, ARTK marks, base stations and static sessions. Also, right clicking any processed epochs accesses the *Object* menu where a host of functions can be found.

☒ The accuracies given are only guidelines. Quality numbers are meant only to provide a high level indication of solution quality. We highly recommend accessing GrafNav's quality control plots for a more in-depth analysis.

Mouse Usage in Map Window

Positioning the cursor on a processed epoch and clicking with the left mouse button accesses a summary of the processing results for that epoch. The time, quality number, number of satellites, standard deviation, forward/reverse separation and other statistics are displayed.

Right clicking on a processed epoch accesses the *Object* menu, which can be used to perform a host of other tasks. See *Section 2.4.7, Objects* on page 39 for more information about the Object menu

If you have a scroll-wheel on your mouse, you can use it to zoom in and out by scrolling forwards and backwards over the area of interest.

Right-clicking on the Map window provides you with several options, including the ability to load a specific solution and to open the Feature Editor.

The *Save to HTML* option generates an HTML file containing a bitmap version of the Map window. These HTML and BMP files are saved to the *HTML* folder contained within the project folder.

See *Section 2.8, Tools Menu* on page 83 for additional interactive mapping tools.



Table 3: Quality Number Description

Quality	Color	Description	3D Accuracy (m)
1	Green	Fixed integer	0.00 – 0.15
2	Cyan	Converged float or noisy fixed integer	0.05 – 0.40
3	Blue	Converging float	0.20 – 1.00
4	Purple	Converging float	0.50 – 2.00
5	Magenta	DGPS	1.00 – 5.00
6	Red	DGPS	2.00 – 10.00
Unprocessed	Grey	Has not been processed	N/A

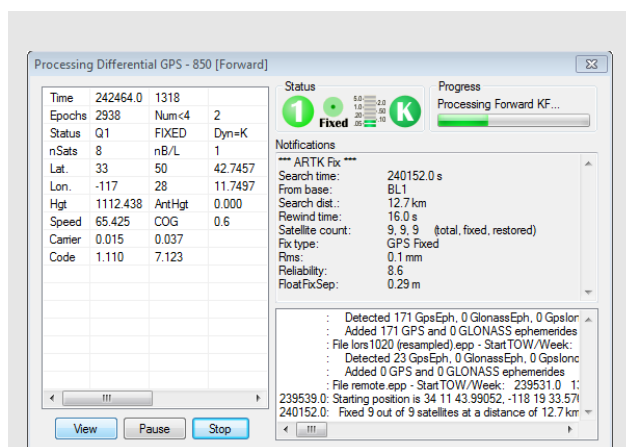


Table 4: Notifications Window Messages

Message	Description
Search time	Time at which ARTK engaged.
From base	Specifies which base station ARTK used to fix ambiguities. This will often be the closest base station in multi-base projects.
Search distance	This is the baseline distance when ARTK was first engaged.
Rewind time	When ARTK achieves a fix, GrafNav can (data quality permitting) apply the integer carrier phase ambiguities backwards in time to the moment ARTK was engaged. The rewind time reports the number of seconds ARTK was able to restore integer ambiguities backwards from the engage time.
Satellite Count	The number of satellites used by ARTK. The <i>total</i> , <i>fixed</i> and <i>restored</i> numbers are reported. <i>Total</i> represents the number used in the float solution. <i>Fixed</i> indicates the number which achieved fixed integers at the restore time. <i>Restored</i> indicates the number of satellites where GrafNav was able to restore backwards in time (see <i>Rewind time</i>)
Fix Type	Solution type used.
RMS	The RMS of an ARTK fix represents how well the carrier phase measurements fit together. Low RMS values (3 mm or less) represent very good fitting solutions. While this does not guarantee a correct solution, it is a good indication. High RMS values (above 5 mm) may still be correct but the chances of an incorrect fix are higher. Regardless, the <i>Combined Separation with Fixed Ambiguity</i> plot can be accessed to help identify incorrect ambiguity fixes.
Reliability	Reliability is a unitless value that indicates how much better the best ARTK fix is from the second best. This is determined by dividing the RMS of the second best fix by the RMS of the best fix. High reliability values (above 3) indicate a high probability the fix is correct as the best ARTK fix appears much stronger than the second best.
FloatFixSep	This is the distance between the fixed integer solution and the last float solution prior to achieving a fix. Large values (meter level) can be expected where ARTK uses only several seconds of data, as the float solution will not be well converged.

2.7.12 Processing Window

This window appears during processing and shows position, status, progress and any high priority messages output by the processing engine.

Click the *View* button to customize the fields displayed during processing. See *Table 3, List of Output Variables* on page 171 for descriptions of variables which can be monitored during data processing.

This screen is updated twice a second.

Status

The status section of the processing window reports the quality number. Quality numbers are meant to provide a high level indication of solution quality and are further described in *Table 3, Quality Number Description* on page 79. The float/fixed ambiguity status is also indicated and as well as a *K* if the processing mode is kinematic or *S* if the processing mode is static.

Progress

The Progress box graphically displays how much of the data has been processed and how much remains.

View

In the left-hand window, various parameters are available for display via the *View* button. The list of available parameters is given in *Table 6, Processing Window Parameters* on page 81.

Notifications

For kinematic processing, the *Notifications* window displays all information pertaining to the last ARTK solution. Descriptions of these messages are found in *Table 4, Notifications Window Messages*.

For static processing, the *Notifications* window displays all information pertaining to the fixed solution. Descriptions of these messages are shown in *Table 4, Notifications Window Messages*. Messages included in the *Notification Window* for static processing are in *Table 5, Notifications for Static Processing* on page 81.

Table 5: Notifications for Static Processing

Message	Information
RMS	Similar to the RMS computed for an ARTK fix, the RMS of a fixed static solution represents the fit of the carrier phase measurements.
Reliability	See <i>Reliability</i> for ARTK fixes in <i>Table 4, Notifications Window Messages</i> on page 80 for a definition. The reliability for long fixed static solutions may be reported as <i>N/A</i> , which indicates that only one fix was within the search area. Thus, there was no second best RMS in order to use in computing reliability.
Frequency	Reported as <i>single</i> or <i>dual</i> to indicate whether an L1 only or L1/L2 solution was computed.
Time	The length of time used by the fixed integer solution in hh:mm:ss format.
Type	Fixed static solution type used. <i>Continuous</i> looks for the best continuous block of cycle slip free data to use within the fixed integer solution. <i>NewFixed</i> (multi-sat) uses all of the data, although it may reject some sections of data for individual satellites.

Table 6: Processing Window Parameters

Parameter	Description
Acceleration Vector	Displays the east, north and height acceleration components in Local Level frame.
Baseline Data (MB)	Displays the distance, carrier phase RMS and number of satellites for each baseline.
Baseline Distance	Distance separation for projects containing only one base station.
Channel (Ambiguity)	Displays the ambiguities, as well as their standard deviation, for each satellite being tracked.
Channel (Az/Elev)	Displays elevation and azimuth for each satellite being tracked, in degrees.
Channel (Flag/Locktime)	Displays the status flag and locktime count for each satellite being tracked.
DOPs	Displays DD_DOP, PDOP, HDOP and VDOP.
Estimated Accuracy	The instantaneous north, east and height standard deviation of the remote position.
Geographic Position	Displays the instantaneous position and antenna height of the remote.
Local Level Vector	Local Level vector in metres.
Measurement RMS	The RMS of the code and phase measurements are displayed, together with their standard deviation (measurement weight) in the Kalman filter.

Parameter	Description
Speed/COG	Speed of the vehicle is displayed with the Course-Over-Ground (COG), computed between consecutive measurement epochs.
Status Flags	Solution quality information such as number of satellites, quality factor and ambiguity status.
Time/Epochs	Displays time in seconds of the week, as well as a continuous count of epochs processed. The GPS week number is also shown.
Velocity Vector	Components of velocity in the Local Level frame.
Channel Data B/L	Allows for selection of baseline for which to display channel information.

2.8 Tools Menu

2.8.1 Zoom In, Zoom Out & Zoom Reset

The *Zoom In* and *Zoom Out* tools adjust the viewing scope of the map, while the *Zoom Reset* brings the map back into the default view.

If you have a scroll-wheel on your mouse, you can use it to zoom in and out by scrolling forwards and backwards over the area of interest.

2.8.2 Distance & Azimuth Tool

The *Distance & Azimuth* tool can be used between epochs, base stations and feature/station marks that are displayed on the Map window. Left click on the feature or epoch that you wish to measure *from* and then right-click on the feature or epoch that you want to measure *to*. The *Distance and Azimuth* window reports the horizontal, surface, grid and spatial distances between the selected points. The azimuth and scale factor information are also displayed.

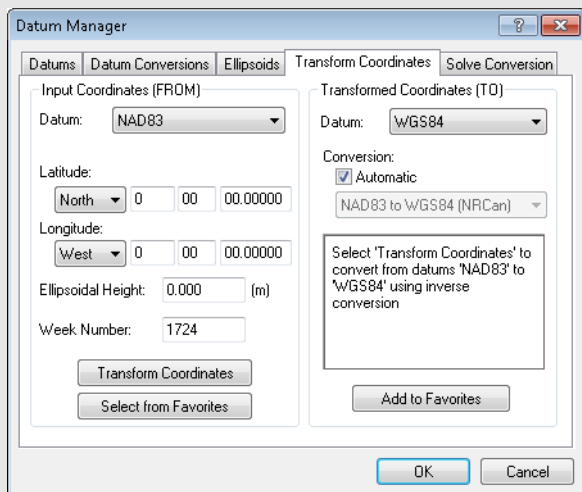
2.8.3 Move Pane

This tool is only accessible provided you have used the *Zoom In* tool to view a smaller portion of the Map window at greater magnification. This tool allows you to access different areas of the Map window without changing the zoom level.

2.8.4 Find Epoch Time

This feature makes it easy to find an epoch on the Map window provided the GPS time in seconds of the week. When used, it circles the epoch in red and if necessary changes the zoom level so that it is in the middle of the Map window.

Zoom In	(+)
Zoom Out	(-)
Zoom Reset	
Distance & Azimuth Tool	
Move Pane	
Find Epoch Time	
Datum Manager	
Geoid	▶
Grid/Map Projection	▶
Convert Coordinate File	
Time Conversion	▶
Favourites Manager	
Mission Planner	
Download Service Data	



2.8.5 Datum Manager

See *Section 2.6.3, Datum* on page 58 for information regarding the first three tabs. The two remaining tabs are discussed here.

Transform Coordinates

Use this tab to transform individual points from one datum to another. If you have a list of points to convert, use the *Convert Coordinate File* option. Points can also be loaded from favourites and after conversion saved back to favourites.

One reason to use this tab is to convert base station coordinates prior to processing. This is not strictly necessary however, as it may be easier to process in the same datum in which your base station coordinates are provided, and if required specify a datum transformation within the Export Wizard.

-
- ☒ Specifying the week number of the coordinate effects the final result if using the conversion 14-parameter.
-

Solve Conversion

Most datum transformations between global datums, such as all realizations of ITRF, WGS84, NAD83, ETRS89 and others, are supported within GrafNav.

Provided official datum transformation parameters, conversion can be added through the *Datum Conversions* tab. Therefore, solving a datum transformation using lists of coordinates, as can be done through the *Solve Conversion* tab, is not a feature that most customers will use or require.

GrafNav can solve 3, 7 and 14 parameter transformations between datums. The 7-parameter transformation can have the scale constrained to unity resulting in a 6-parameter transformation with 3 translations and 3 rotations. The 14-parameter transformation solves scale, scale rate, translation, velocity, rotation, and rotational rate. This requires that lists of coordinates be available in both datums. The two lists must be in ASCII format and all points in each file must be common to both files, with identical point names. The order the points appear in each file is not important and ellipsoidal height values are required.

-
- ☒ 7 and 14-parameter transformations should only be used for areas greater than 300 km² because solving transformations over small areas makes the parameters very sensitive to coordinate errors.
-

14-parameter transformations require each file to provide two coordinates for each point at different epochs.

Advanced Settings

Add computed conversion to Datum Conversion List

Adds the computed conversion to the list under the *Datum Conversions* tab. This allows the conversion to be used by the software.

Force scale factor to 1.0

Constrains the PPM scale to zero (scale factor = 1). This is only applicable for the 7-parameter.

Compare against existing conversion

Computes residuals for another existing conversion in the *Datum Conversions* list. This is useful for determining if the newly computed conversion fits better than the existing one.

Processing Report

The following are contained in this report:

Parameters

The input options used for the computation.

Raw Differences

These are the raw differences between the ECEF coordinates of the matched points in the two files. Only points that have a match found are processed. The *USED* column indicates if points are to be used in the solution or not and refers to the *Flag* in the *FromDatum* file.

Transformation Parameters

Shows the parameters computed by the solve process. If a comparison is made, then this shows the parameters from the datum conversion. If the transformation needs to be inverted due to opposite *From* and *To* datums, then the reversed values are shown.

Residuals using ...

Shows the difference between raw *FromDatum* coordinates and the *ToDatum* coordinates transformed into the *FromDatum*. Root-mean-square values are shown at the bottom. Note that the residual values are oriented to local level (east, north and up).

Raw Differences

These are the raw differences between the ECEF coordinates of the matched points in the two files. Only points that have a match found are processed. The *USED* column shows if points are to be used in the solution or not and refers to the *Flag* in the *FromDatum* file.

2.8.6 Geoid

Geoid files are required when exporting Mean Sea Level (MSL) heights. Geoid files contain a grid of undulation values that represent the difference between ellipsoidal and MSL height. To calculate MSL height from ellipsoidal height at any geographic position, GrafNav subtracts an interpolated geoid height (undulation value) from the ellipsoidal height. A Lagrange interpolation method is used.

Waypoint software supports a proprietary WPG geoid format. All publicly available geoids (in WPG format) that NovAtel is permitted to re-distribute can be found in the **Waypoint Geoids** section of the NovAtel website. We also provide utilities to create WPG files from ASCII files and other known formats in order to create custom or local geoids.

Every GrafNav project requires ellipsoidal base station heights. This is because the geoid is a complicated mathematical surface, and all data processing needs to be performed relative to the ellipsoid. However, the *Enter MSL Height* feature on the *Master Coordinate* dialog permits you to work directly with MSL heights. This works by back-calculating an ellipsoidal height provided an MSL height and a geoid file.

Regardless of how you have entered your base station coordinates (i.e. if you have directly entered an ellipsoidal height or if you have used the *Enter MSL height* feature), the Export Wizard will prompt you for a geoid if your export profile contains MSL heights.

The *Information* feature can be used to access basic properties of a geoid in WPG format including the datum and geographic boundaries. When using a datum, be careful to ensure your processing datum is the same as the geoid datum.

The *Compute Geoid Height* feature allows you to calculate the geoid height for individual coordinates. If you have a list of coordinates to convert from ellipsoidal to MSL (or vice versa), use the *Convert Coordinate File* feature.

2.8.7 Grid/Map Projection

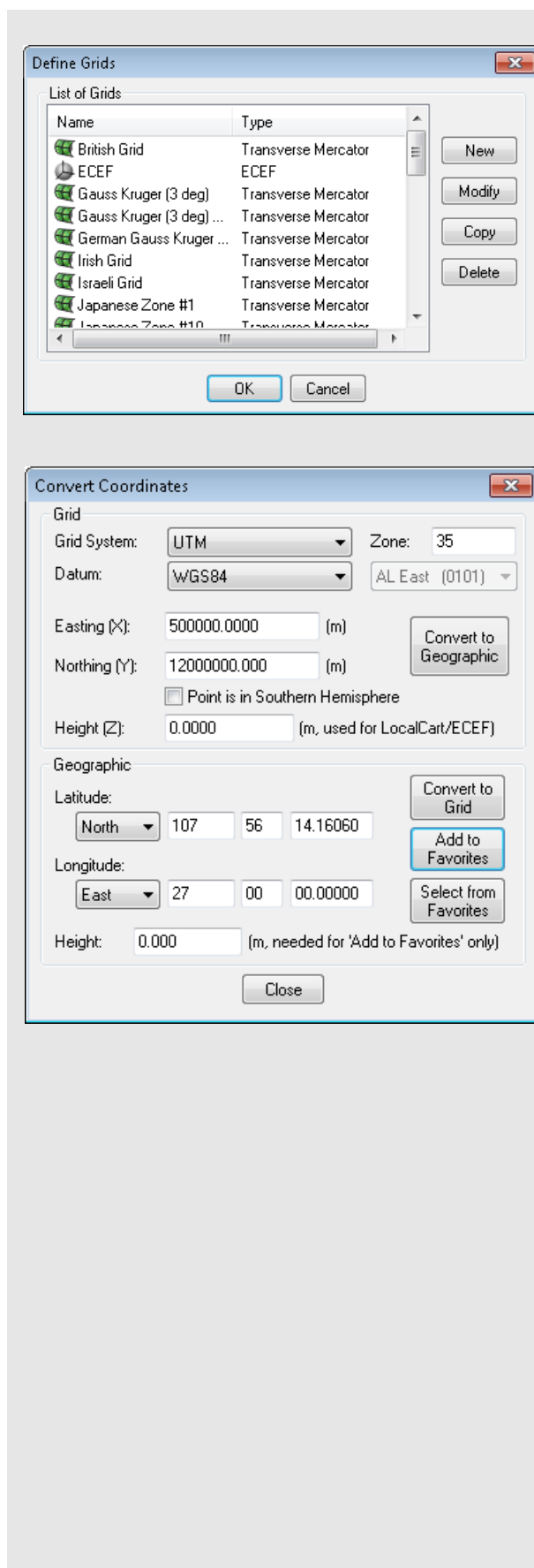
GrafNav supports grid/map projections in several ways including the following:

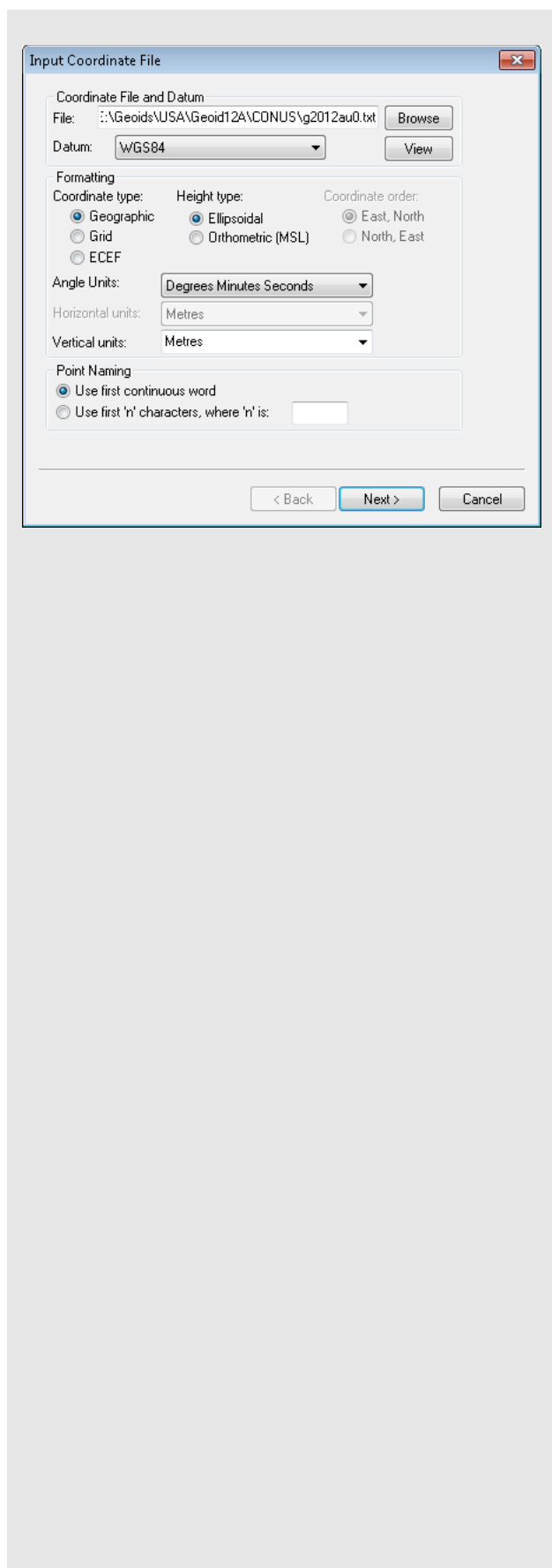
- The *Enter Grid Values* feature on the Master Coordinate dialog allows you to enter horizontal base station coordinates in any defined grid.
- You can output final coordinates in a map projection of your choice. See *Section 2.6.8, Preferences* on page 61 and *Section 2.7.11, Show Map Window* on page 79 for additional information.
- Several grids, like UTM, TM, Gauss Kruger, US State Plane and Lamber, have been pre-defined in the software. However, you can also add your own by selecting *New* within the *Define Grids* dialog as shown on the right.
- Use the *Transform Coordinates* tool under *Tools | Grid/Map Projection* to convert between geographic coordinates and grid coordinates.

Transform Coordinates

This tool transforms coordinates for a single point from geographic to grid, or vice versa. When transforming TM projections, make note of the *Point is in Southern Hemisphere* option; it is disabled by default.

-
- ☒ After a conversion from grid coordinates to geographic coordinates has been made, you may add them to your *Favourites*.
-





2.8.8 Convert Coordinate File

This tool takes an ASCII file containing a list of coordinates as an input and outputs an ASCII file to a different datum or format. You can use this utility not only to convert between datums, but also to change the format of a file. For example, you can convert an input list of coordinates from geographic to ECEF, or a list of coordinates with ellipsoidal heights or MSL.

The *Use first continuous word* option is the default. If the station names contain spaces, select *Use first 'n' characters*. The sign conventions used for geographic coordinates is positive for the northern and eastern hemispheres and negative for the southern and western hemispheres.

Additional options seen on the screen just before generating the output file include the following:

Include column header

Conserves the header information from the input file.

View output files after conversion

Automatically opens the output file after clicking *Finish*.

Input grid coordinates in southern hemisphere

Only necessary if the input data has grid coordinates from a project area that is in the southern hemisphere.

Do not apply datum transformation to height

This option is useful for outputting orthometric heights because no datum transformation are applied in this case.

2.8.9 Time Conversion

This tool converts GPS seconds of the week to hh:mm:ss format (GMT), provided a GPS week number.

Alternatively, hh:mm:ss (GMT) can be converted to GPS seconds of the week, provided a month, day and year has been specified.

2.8.10 Favourites Manager

GrafNav's Favourites Manager is used to store known coordinates for GPS reference stations. This permits easy retrieval without the risk of data entry errors through the *Select From Favourites* feature of the master coordinate dialog.

GrafNav's Favourites Manager comes pre-loaded with coordinates for three GNSS networks. NAD83(2011), NAD83(CORS96) and IGS08 coordinates are provided for stations on the CORS network. CORS (Continually Operating Reference Stations) is a network of receivers managed by the National Geodetic Survey (NGS). CORS stations are most commonly found in the USA, although a relatively small number of stations operate in other countries as well.

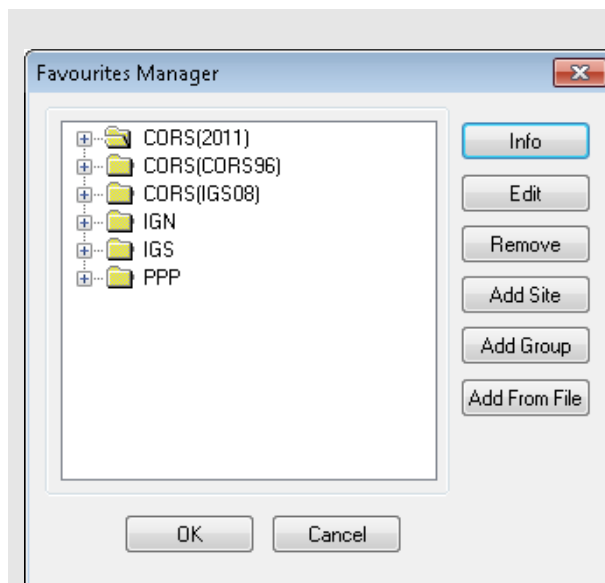
Also found in the Favourites Manager are RGF93 coordinates for the IGN network. IGN stations are found in France.

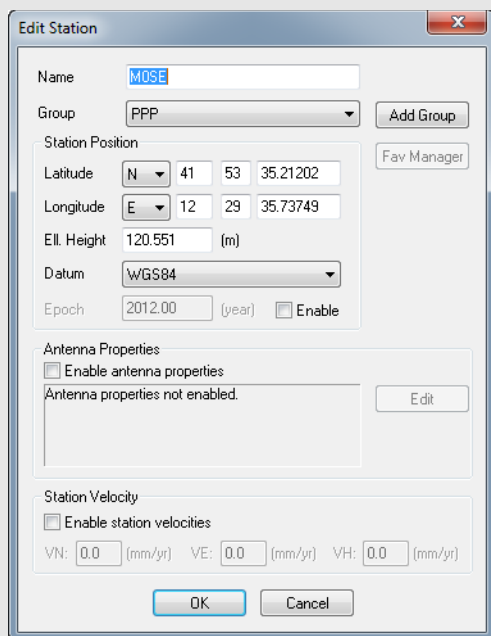
Lastly, ITRF05 coordinates are stored for stations on the IGS network, which is managed by the Scripps Orbit and Permanent Array Center (SOPAC) and provides access to many different networks worldwide.

The Favourites Manager and the Download Utility are complimentary in the sense that the latter provides access to base station data through anonymous FTP and the former ensures precise coordinate and datum information is loaded into your GrafNav project.

Both utilities (the Favourites Manager and the Download Utility) are updated on a monthly basis by Waypoint support staff in order to ensure the list of stations (which is constantly growing) and coordinates is kept current. GrafNav will attempt to automatically download the latest manufacturer files on a bi-weekly basis to ensure they are kept up to date.

In addition to pre-loaded favourites for specific networks, users can create their own favorite groups in order to store their own surveyed base station locations.





Edit Station

Name:

Group:

Station Position

Latitude:

Longitude:

Ell. Height: (m)

Datum:

Epoch: (year) ☐ Enable

Antenna Properties

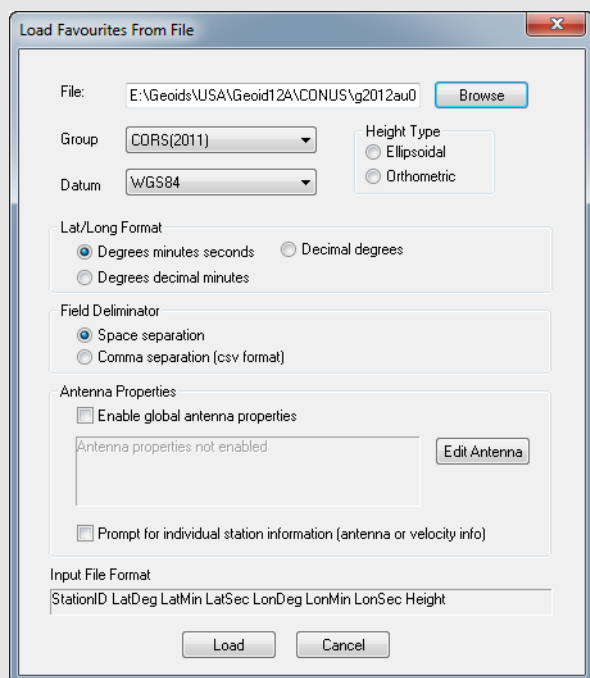
☐ Enable antenna properties

Antenna properties not enabled.

Station Velocity

☐ Enable station velocities

VN: (mm/yr) VE: (mm/yr) VH: (mm/yr)



Load Favourites From File

File:

Group:

Datum:

Height Type

☒ Ellipsoidal

☐ Orthometric

Lat/Long Format

☒ Degrees minutes seconds ☐ Decimal degrees

☐ Degrees decimal minutes

Field Delimiter

☒ Space separation

☐ Comma separation (csv format)

Antenna Properties

☐ Enable global antenna properties

Antenna properties not enabled.

☐ Prompt for individual station information (antenna or velocity info)

Input File Format

StationID LatDeg LatMin LatSec LonDeg LonMin LonSec Height

The following options are available in the *Favourites Manager* via the buttons on the right-hand side:

Info

If clicked while a group is highlighted, this returns the total number of sites contained within the group.

If clicked while an individual site is highlighted, the position, velocity and datum are displayed.

Edit

Use this option to modify the information related to a station, including coordinates, antenna information, and station velocities.

Remove

Use this option to removed an individual site or an entire group.

Add Site

Use this option to add a new site into any group.

We recommend creating a custom group prior to adding your own sites.

Add Group

Use this option to add of a new group.

Add from File

Using this feature, a list of station coordinates can be directly loaded from an ASCII file, eliminating the need for manual entry. The file must contain the station names and coordinates in a comma- or space-delimited format. The *Input File Format* box at the bottom of the window provides a useful reference for those users who are unsure as to what their input file should look like.

☒ Southern latitudes and western longitudes should be denoted by a negative sign.

Information regarding the stations' antennas can also be specified here. If the antenna model and/or heights are common to all the stations being added, then the *Enable global antenna properties* setting can be enabled to specify this information. If the information varies from station to station, then the *Prompt for individual station information* option should be enabled. This latter option is also needed if you wish to specify station velocities.

2.8.11 Mission Planner

The mission planner is used to predict GPS or GPS+GLONASS constellation information ahead of time. Number of satellites, DOP (HDOP, VDOP and/or PDOP), and other information can be plotted provided a location, date, and other basic parameters (including an elevation mask, start and length).

Mission planning is typically performed in order to determine if there are any particular periods of the day that should be avoided (if possible) due either to low number of satellites or poor satellite geometry.

While four GPS satellites are required to compute position, six GPS satellites is the recommended minimum for high accuracy applications. This is because six satellites is the minimum needed for GrafNav's outlier detection routines to function in the event high measurement residuals are detected.

When examining predicted PDOP, one factor to consider is that ambiguity resolution becomes more challenging when PDOP values approach 3.

Settings

Mode

Single Point predicts satellite geometry for a single point of operation (i.e. a single latitude and longitude).

Only consider using *Differential* mode if your base station is very distant from your project area (100+ km).

Differential mode predicts the satellite constellation considering which satellites are simultaneously available at both locations.

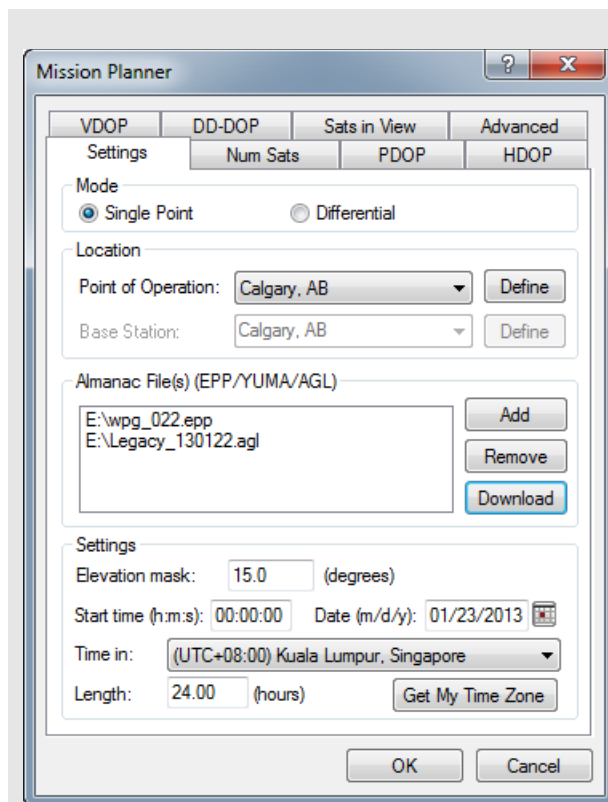
Point of Operation

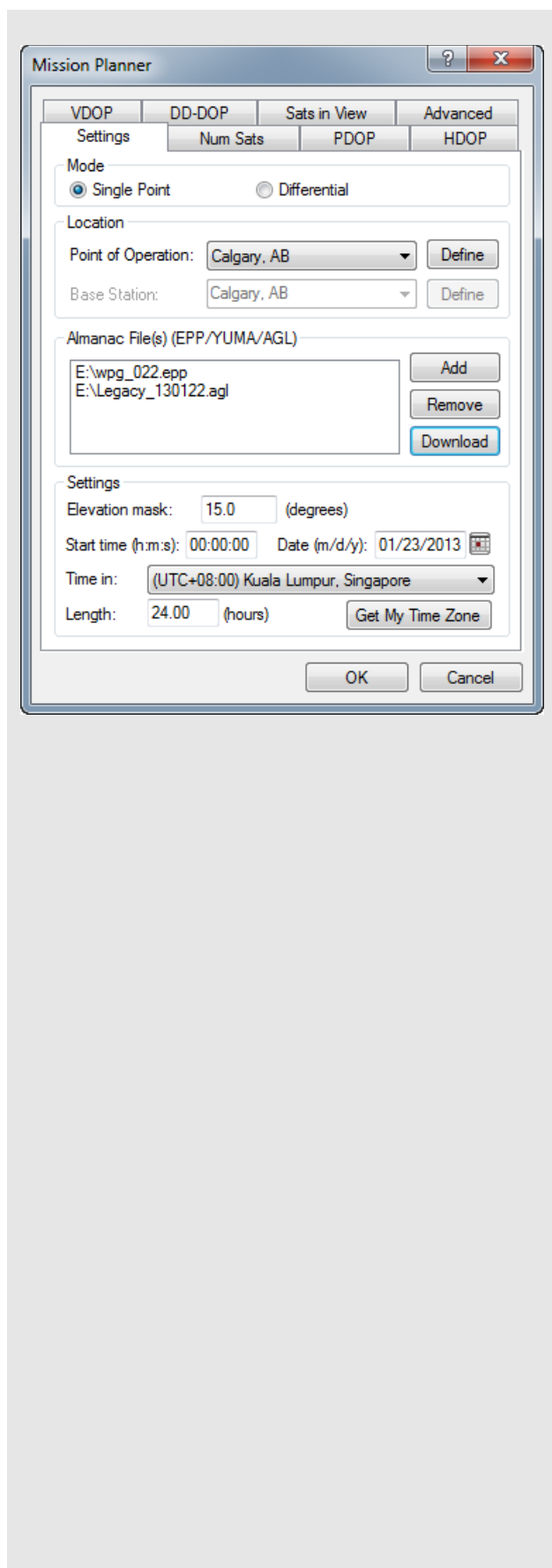
Click *Define* to select either a station from one of the pre-defined lists (lists of North American or Worldwide cities) or to define your own location.

Two default files (MPF) are provided with the software. The first is *north_am.mpf*, which contains an extensive list of North American cities. The second is *world.mpf*, which includes cities from around the world. There is third file available, *MissPlan.mpf*, for users who wish to create their own list of geographic locations.

Base Station

Only available if *Differential* has been selected under *Mode*.





Almanac File(s)

GPS and GLONASS almanac files permit the Mission Planner to compute predicted satellite orbits.

Almanac files can be downloaded, provided an internet connection, or a Waypoint ephemeris file (epp) can be used if almanac data was logged during data collection. The latter option applies only to NovAtel receivers.

If you already have a valid almanac source, use the *Add* button to locate it on your hard drive. Otherwise, use the *Download* button to bring up the *Download Almanac Files* window, from which you can specify the date and constellation for which the almanac data is needed. If you are Mission Planning for a future date (as is most often the case), the date shown in the *Download Almanac Files* dialog will be yesterday's date. Yesterday is used because the almanac files from yesterday are likely to be available for download (i.e. if you attempt to download almanac files for today's date, it may fail if the files have not already been uploaded).

Settings

The following settings are available:

Elevation mask

Only satellites above this elevation mask are considered when computing numbers of satellites and geometry. In general, it is good practice to use a slightly higher elevation mask than you typically apply in post-processing.

Start time

The start time of the mission. Used as the starting point for all displayed plots. Ensure to also select the correct time zone.

Date

The date of the mission.

Time in

Use the *Get My Time Zone* button to specify your local time offset from GMT. If you are mission planning for a project outside your time zone, use the drop-down list to make a manual selection. Note that all plots will display *H:M:S* time in the local time frame.

Length

Determines the time span that is covered by the displayed plots.

Num Sats PDOP, HDOP, VDOP, and DD-DOP

The following descriptions are applicable to the *Num Sats*, *PDOP*, *HDOP*, *VDOP*, and *DD_DOP* tabs.

Chart Type

Select *None* to tell the utility not to plot the values associated with the current tab. By default, *None* is selected for the HDOP tab, VDOP tab, and both plots under the *Sats in View* tab. If any of these charts are of interest, they need to be enabled by selecting either the bar chart or line graph options. The Mission Planner will by default show only the number of satellites and PDOP plots.

The main difference between the bar chart and the line graph is that the latter distinguishes between GPS and GLONASS. That is, you will be able to determine how many satellites are available from each constellation and not simply a total number, as would be reported in the former.

Bar Color

Applicable only to the bar chart format. This feature also permits colors to be customized by adjusting minimum and maximum ranges.

Y-axis Range

Select *Automatic* to force the *Mission Planner* to automatically scale the Y-axis for each plot. Manually enter the boundaries by selecting *Manual*.

Satellites in View

Chart Type

Select *None* if you do not want to view this plot. Otherwise, you can select *Satellite lock plot*, which allows you to view an elevation plot of the satellites in view.

Satellite Sky View Plot

Displays a plot that shows the elevation and azimuth of all satellites over time.

Advanced Tab

Log File

You can choose to save an ASCII output of the mission planning information. Enable *View LOG file after processing* to open this output file when plotting is finished.

Data Interval

Select *Automatic* to force the *Mission Planner* to compute a data interval suitable for most recent plot window size. Select *Manual* to define a data interval to improve the resolution.

Options

The options that are available are listed in the shaded box.

Num Sats PDOP, HDOP, VDOP, and DD-DOP Options

Ignore satellites with bad health

Mission Planner checks the almanac file for any sick satellites if this option is selected. Any satellites confirmed as being so are removed from plotting and output.

Ignore these satellites

If certain satellites are causing problems, but are not identified as being sick in the almanac file, they can be manually specified here for removal from plotting and output.

Plot all DOPs on one graph

If multiple DOP plots were requested for viewing in line graph format, enabling this option forces them to be displayed on the same plot.

Display seconds of the GPS week instead of H:M:S

Toggles the format of the X-axis labeling between GPS seconds of the week or Local *H:M:S*.

☐ If any changes were mistakenly saved in *Mission Planner*, the defaults can be restored by deleting the *WPMissPlan.ini* file in the *C:\Windows* directory.

System Usage:

GPS only -restrict to GPS satellites

GPS + GLONASS - both systems if both almanacs are loaded

Satellite systems to use

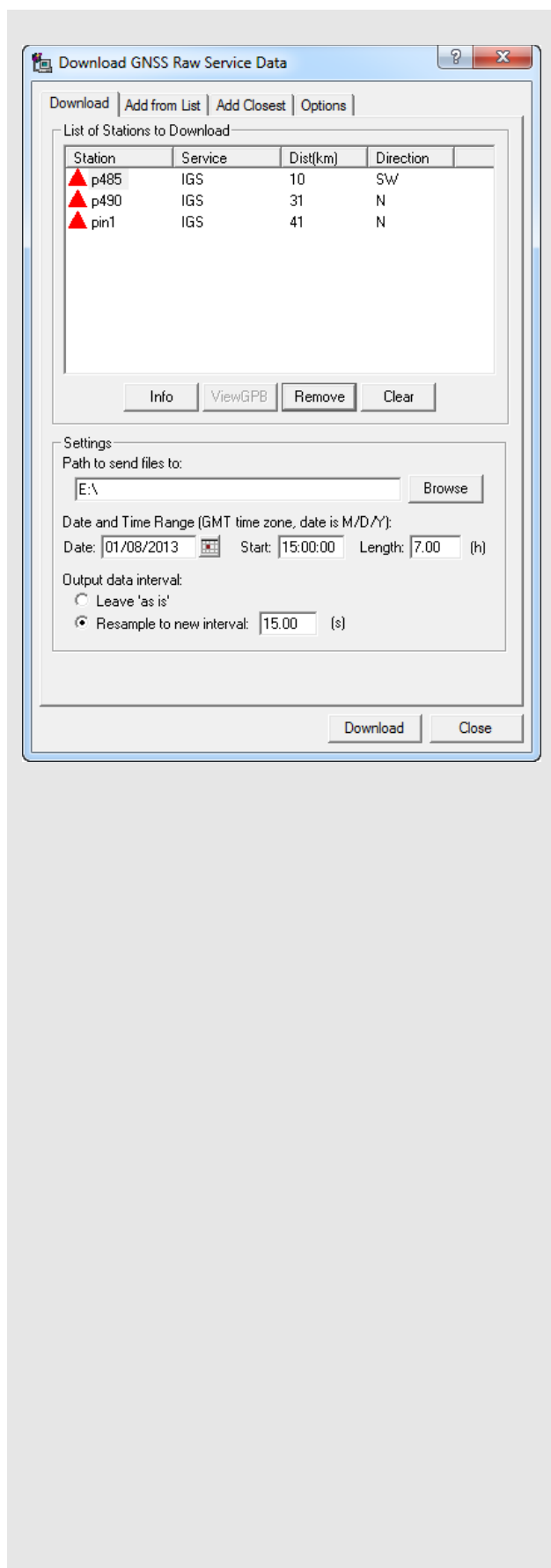
Specifies the constellation(s) for which you need the predictions made.

GLONASS PRN offset

GLONASS PRN numbers will vary depending on the receiver. An offset can be entered here to match that used by your receivers.

UTC time offset

Specifies the difference, in seconds, between the UTC and GPS time frames.



2.8.12 Download Service Data

The Download Service Utility facilitates downloading, converting, and if needed concatenating and resampling of GNSS base station data.

There are currently 19 supported networks, providing access to thousands of publicly available base stations worldwide. Waypoint provides a KML file for all supported networks within the **Waypoint Downloads** section of the NovAtel website.

The *Add Closest* tab can be used to search for base station data provided a converted GPB file that you wish to process. This function not only reports a chronological list of the nearest stations, but also automatically scans the date, start/end times, path to download the files to and sampling rate of the GPB file.

The download utility can be used not only to quickly retrieve GNSS base station data, but also to download precise ephemeris and clock files, almanac files, additional broadcast ephemeris data and other data (see the *Options* tab).

Download

List of Stations to Download

This displays a list of the stations that have been selected for download. The list is empty until you add to it using the *Add from List* or *Add Closest* tabs.

Settings

The *Path to send files to* field specifies where to save the downloaded files. The *Date and Time Range* parameters indicate the date and time range (GMT) of the data to be downloaded. If using the *Position from GPB file* option on the *Add Closest* tab, all of the parameters under *Settings* are scanned automatically.

Selecting *Leave 'as is'* will not perform any type of resampling on the downloaded data. Select this option if you are processing static data only (such as in GrafNet). Common sampling rates provided by GNSS networks are 1, 5, 10, 15 and 30 seconds. Some networks, such as CORS, only make high rate available for a limited period of time (such as 30 days) prior to archiving the data at a 30 second sampling rate. Therefore it is good practice to retrieve base station data within days of your survey when possible.

In differential processing, only common epochs can be processed between master and remote. Thus when processing kinematic data, it is required to resample base station data to the same interval as your remote prior to processing.

When resampling, additional noise is introduced in the resampled epochs. The magnitude of the added noise is dependent on the original sampling rate of the data.

Waypoint has found that the amount of noise introduced when resampling from an original rate of 5 seconds is negligible. When resampling from 30 seconds however, 1-2 cm of noise (RMS) can be introduced. This may only be significant for very high accuracy applications.

Add From List

List of Stations

This window provides an alphabetical listing of all services. Expand the list to show the individual stations within each service. The *Info* button provides an approximate coordinate, which is used when searching for base station data using the *Add Closest* tab. The *Add* button places the station on the *List of Stations to Download* under the *Download* tab.

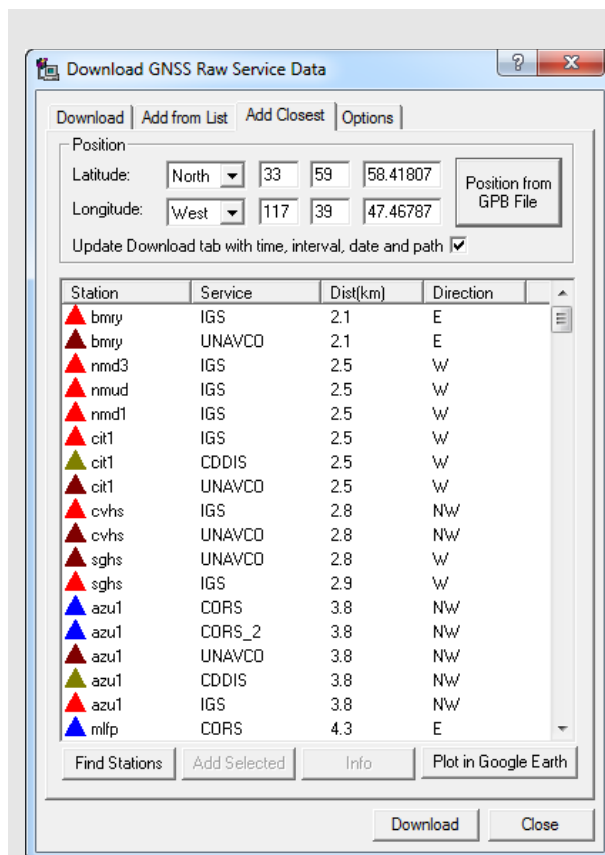
Download Latest List

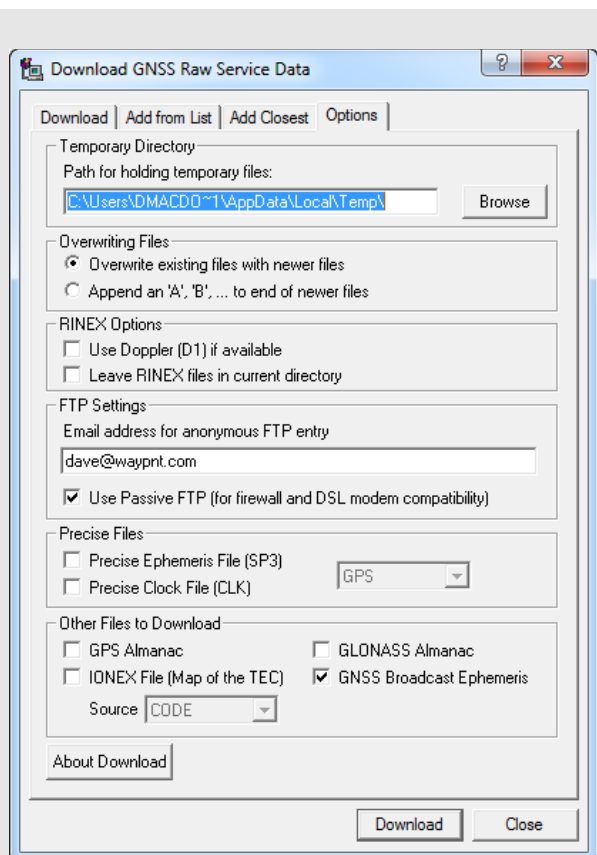
This connects to the Waypoint FTP site and downloads the most recently updated manufacturer's files for the version you are using. Waypoint updates the list of stations on a monthly basis.

Add Closest

This tab reports the distance and azimuth using either a user entered location (if directly entering a geographic position) or relative to the position records scanned from a GPB file.

If using the *Position from GPB File* function, the download utility searches your file at regular intervals and will report the minimum distance to each base station at any point in the trajectory. This is more helpful than taking an average of the GPB position records for large project areas.





Specified correction files

IONEX File

Contains information regarding the total electron count (TEC) of the ionosphere. This is useful in single frequency processing to help reduce ionospheric error. IONEX data is not helpful to, and thus not applied, if dual frequency processing is used.

GPS Almanac

Can be used in conjunction with the Mission Planner in order to predict GPS satellite geometry.

GLONASS Almanac

Can be used in conjunction with the Mission Planner in order to predict GLONASS satellite geometry.

GNSS Broadcast Ephemeris

Downloads a global RINEX file for the date(s) specified in the Download tab and converts to Waypoint's EPP file format. Can be used to supplement missing ephemeris data in a GrafNav project.

Options

There are several settings under this tab which require proper configuration in order for the *Download Service Data* utility to function properly.

Temporary Directory

The directory specified here temporarily stores RINEX files while they are being converted into GPB format.

Overwriting Files

If a file already exists in the destination directory with the same name as the file being downloaded, this setting determines which action to take. *Overwrite existing files with newer files* replaces the file with the one being downloaded. *Append an 'A', 'B' to end of newer files* renames the new file to avoid conflict.

RINEX Options

Leave raw RINEX files in Current directory

May be selected if you do not wish to have the RINEX files deleted after conversion to GPB.

FTP Settings

The FTP sites accessed with this utility are public and accept anonymous login. To do this, provide an email address to be used as a password for login. Users with a DSL connection, or behind a firewall, might have to enable *Use Passive FTP* for this utility to connect properly.

Precise Files

Precise ephemeris and clock data can be downloaded from sources that provide GPS only data, or sources that provide both GPS and GLONASS data by accessing the pull down menu. Downloading products that contain both GPS and GLONASS data is important when collecting GLONASS data, as otherwise GLONASS will be excluded from the results.

Precise ephemeris and clock data are required for PPP processing in order to correct for metre level errors. Precise ephemeris data is optional in differential projects as much of the orbital error is cancelled, as the line of sight component of satellite orbital error is correlated with baseline length. Differential projects involving baseline lengths in excess of 150+ km may benefit from the inclusion of precise ephemeris.

Other Files to Download

Any files selected here are downloaded for the day(s) specified on the *Download* tab. You can specify any of the correction files listed in the shaded box for download.

Add Stations and Services

The services currently found within the download utility are supported because they provide public access to data and they are known to us.

If you know of another service which provides public FTP access to GNSS reference data, contact Waypoint support (support@novatel.com) as it may be possible to add the service to the software. This has the added benefit of making the service available to all other GrafNav users as well.

If you prefer to add your own custom service, create a *user.dn1* file within your User directory. The exact location of this directory can be found from the *All user created or modified..* section of the *Update* tab within *Settings | Preferences*.

Station records must conform to the format in the shaded boxes on this page and the next page.

-
- ☒ You might find it easier to copy a station record from the *manufact.dn1* file and paste it into *user.dn1* file for modifying.
-

Adding a service requires knowledge of the FTP address at which the data is stored. The directory structure and file type must be known.

Station record format

```
Station { sName:      Four-character station name as
                      saved on FTP server. See Note 1
                      on page 98.
          lat:        Latitude, in DMS, followed by N
                      or S to designate hemisphere.
          lon:        Longitude, in DMS, followed by E
                      or W to designate hemisphere.
          ht:         Ellipsoidal height, in metres.
          serv:       Name of service to which the
                      station belongs. See Note 1 and
                      Note 3 on page 98.
        }
```

Service record format

```
Service { ServId:    Name of service, up to a maxi-
                      mum of 8 characters. See Note 1
                      on page 98.
          ftpAd:      Address of the FTP server.
          User Name:  Required to log into non-public
                      sites. See Note 1 and Note 4 on
                      page 98.
          Password:   Required to log into non-public
                      sites. See Note 1 and Note 4 on
                      page 98.
          oFile:      Generic path to the observation
                      file. See Note 6 page 98.
          dFile:      Generic path to the compressed
                      observation file. See Note 4 and
                      Note 6 on page 98.
          nFile:      Generic path to the GPS
                      navigation file. See Note 6 on
                      page 98.
          gFile:      Generic path to the GLONASS
                      navigation file.
          hoFile:     Generic path to the hourly obser-
                      vation files. See Note 4 and Note
                      6 on page 98.
          hdFile:     Generic path to the compressed
                      hourly observation files. See Note
                      4 and Note 6 on page 98.
          Ftype:      Type of compression used for
                      files. See Note 2 and Note 4 on
                      page 98.
          Datum:      Datum in which the station posi-
                      tions for this service are defined.
          color:      Color to use for symbols in utility's
                      interface. See Note 4 and Note 5
                      on page 98.
        }
```

Station and Service record notes

- ✉ 1. This field is case-sensitive.
- 2. Only the Z, GZ, and ZIP formats of compression are supported.
- 3. The service name must match the *ServID* field of a service record, as defined in the *manufact.dn1* file or, if the service is user-created, in your *user.dn1* file.
- 4. This field is optional and, thus, does not need to be present.
- 5. The color defined here is used in the interface to identify the stations belonging to this service. The following colors are available: red, green, blue, magenta, cyan, gray, wine, black, gold, darkgray, darkgreen, darkblue, lightcyan, and darkmagenta.
- 6. This field identifies the format of the directory structure used on the FTP site to organize the data. Any folders in the structure that are common to all data must be hard-coded into this field. The rest, however, must be defined using the following case-sensitive strings:

<JJJ> *Julian Day*
 <YYYY> *Year*
 <XXXX> *Station ID*
 <week> *GPS week*
 <wkrl> *GPS week - 1024 - padded with leading zeroes*
 <wkrr> *GPS week -1024 - without padding*
 <yy> *Last two digits of the year*
 <d> *Day of the week (0 – 6)*
 <MN> *Month number*
 <DM> *Day of the month*
 <H> hour of the day, in upper case (A-X)
 <II> hour of the day, numeric (00-23)
 <mmm> first three letters of month (Jan-Dec)
 <CITY> any custom string (such as the name of a city or region) contained within an FTP sites folder structure that varies for individual stations

Service records must conform to the format in the shaded box. Refer to the *manufact.dn1* file for examples of service and station records.

2.9 Window Menu

This menu option displays the GrafNav windows in different ways.

2.9.1 Cascade

Cascades the windows from the top left to the bottom right of the screen.

2.9.2 Tile

Gives each window a section across the screen.

2.9.3 Next and Previous

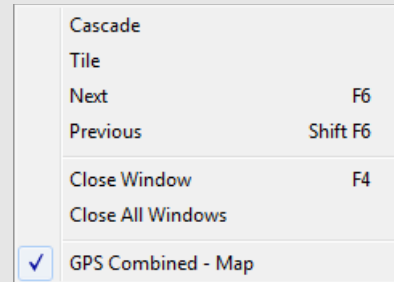
Lets you view one window at a time.

2.9.4 Close Window

Closes one window at a time.

2.9.5 Close All Windows

Closes all windows except the Map window.



List of files downloaded when manufacturer files are updated

manufact.dcb

List of the differential code biases, in nanoseconds, between the P1 and C/A code for each satellite. Used by PPP.

manufact.dn1

List of base stations available for the *Download* utility. This is usually updated monthly.

manufact.dtm

List of datums, ellipsoids and transformations between datums.

manufact.fvt

List of *Favourites* and the groups they are contained in.

manufact.grd

List of available grids such as UTM, US State Plane, Gauss Kruger and so on. See *Section 2.8.7, Grid/Map Projection* on page 87 for more details.

manufact.svi

A file that associates a PRN number with a satellite type (Block II, Block IIA and so on) for purposes of determining the center of mass of the satellite. Used by PPP.

2.10 Help Menu

2.10.1 Help Topics

Opens an HTML version of this manual. This feature can be very useful as a quick and easily accessible reference.

2.10.2 Check for Update

Provided an internet connection, this feature checks the Waypoint server to see if any GrafNav updates are available. If so, they can be directly downloaded and installed.

2.10.3 Download Manufacturer Files

Provided an internet connection, use this option to download the latest manufacturer files from Waypoint's FTP site. The files downloaded when updating are listed in the shaded box.

2.10.4 NovAtel Waypoint Products

This option opens the Waypoint Products page in your default web browser. From here, more information on Waypoint Products can be found, including information regarding the latest version, notices of training seminars, links to FAQ/training materials and technical reports.

2.10.5 About GrafNav

This window displays information about the software version, build dates, copyright information, hardware lock key information and DLL information.

Access the hardware key utility from this window by clicking *Key Util (Upgrade)*. This tool is useful if an upgrade needs to be performed on the hardware lock. The *Dependent Files* window displays a list of executables and DLLs associated with GrafNav. The date and time of the files are shown, as well as a quick description of the file. Other programs have this feature as well.

3.1 GrafNet Overview

GrafNet is a batch static baseline processor and network adjustment package. It is used to establish or check base station coordinates for later use within GrafNav, or survey entire static networks. GrafNet accepts GNSS data only, no terrestrial observations can be imported.

GrafNet is included with both GrafNav and Inertial Explorer, however can also be purchased separately as *GrafNav Static*. This chapter includes examples of networks that are commonly processed in GrafNet, as well as step-by-step instructions for first time users.


3.1.1 Types of Networks

Closed Loop Network


Surveyors often use this style of network because of increased reliability. Due to the closing of the loops, any baseline determination errors will show up as tie point errors. Such closure values can be seen via *Process | View Traverse Solution*. If just two GPS receivers are employed, then a method called “leap-frogging” can be used to collect the data. In this procedure, starting from a known point, the lead receiver is placed on the first point to be surveyed. After the first session is complete, the trailing receiver is moved ahead of the lead receiver so that it now becomes the lead. The next baseline is observed and this procedure is repeated until small (4-6) loops are closed.


Radial Network

Also referred to as *Single Base Station*. Applications where productivity is more important, like GIS, do not need the same degree of reliability as the closed loop network. For these situations, use open loop networks. An example of this a network is in the shaded box. For this method, one receiver is left stationary over a reference or control point. One of more remote GPS receivers are moved from point to point being surveyed.



GrafNet
 Version 8.50
Static Network Post-Processing Software
 8 50 2123
 Copyright NovAtel Inc. 1994-2013



Precise thinking


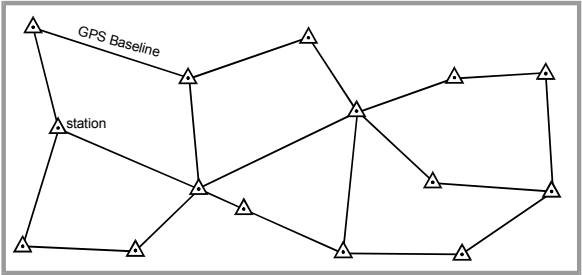


Figure 1: Closed Loop Network

✉ Antenna height measurement errors will often cancel with this method and should therefore be double-checked. Methods involving more than two receivers become quite complex, and are past the scope of this chapter.

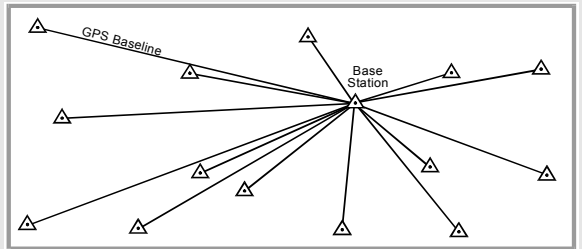


Figure 2: Radial Network

Table 11: Solution Types

Solution Type	Fixed Integer	Ionospheric Correction	Description
L1-Float	N	N	L1 float solution. Used most often with single frequency receivers on short occupations or long baselines.
L3-Float	N	Y	Ionospheric-free float solution. Requires dual frequency but can have very good accuracies on longer baselines if occupation is long enough.
L1-Fixed	Y	N	L1 fixed integer solution. Can be very accurate on shorter baselines. Solution is computed from one continuous period of GPS data with the most satellites covering the longest time. The <i>Message Log</i> (FML / RML) file can be viewed to determine how many satellites are used and for how long.
L1-NewFixed	Y	N	L1 fixed integer solution that uses all of the satellites tracked. Satellite tracks (that is satellite-base pair between cycle slips) that fit poorly are rejected. Look at the FSS / RSS file to view each track.
L1L2-Fixed	Y	See Note	Same as L1-Fixed except that dual frequency data is used. By using the wide-lane, much shorter fix times are possible. For longer baselines, the iono L2 noise model can be used to improve accuracy.

☒ Ionospheric correction is applied if the *Iono Noise* model is used, which depends on the baseline distance, or if you manually select the *L2 Noise* model. In such cases, the solution type appears as *L1L2-IonoFixed* or *L1L2-IonoNewFixed*.

3.1.2 Solution Types

GrafNet automatically determines concurrent sessions by examining the start and end times of the observation files. GrafNet tries to form sessions using an extended time scale to resolve any conflicts stemming from differing week numbers. This requires that a valid ephemeris file (EPP) be present for each corresponding observation file (GPB). For more than two receivers simultaneously collecting data, unwanted session connections can be ignored using the *Session Menu*, under *Process | View All Sessions*. The vector for each session is resolved independently. There are three modes of static processing, including the following:

Fixed Solution

This process uses single or dual frequency data, but assumes integer ambiguities. This mode delivers the best accuracies and is also the default static processing mode. Single frequency will fix reliably on baselines less than 10 km, while dual frequency will work well up to 25 km. Longer baselines require longer observation times.

Float Solution

This method does not solve for integer ambiguities, and therefore, has no baseline length restrictions. Regardless, long single frequency baselines will have much poorer accuracies than their dual frequency iono-free counterparts. Normally, the float solution is only used when either fixed static solutions cannot be made to pass or for single frequency baselines of 10 km or more.

Iono-free Solution

This is a float solution with the ionospheric effect largely removed from the carrier phase by combining L1 and L2 carrier phases in the iono-free combination. This option requires dual frequency data at both stations. Iono-free should normally be used if the fixed solution fails (on longer baselines), or on very long baselines (greater than 50km) where fixed static is unreliable.

GrafNet also offers an *Automatic* mode, which chooses between the three processing modes by examining baseline lengths and the type of measurements available. *Table 11, Solution Types*, in the shaded box, contains a list of solution types attainable in GrafNet.

After processing, baselines will be green if they passed or red if they failed. If an error occurred and only an approximate 1-5 metre solution was extracted, the baseline will show up as purple. If the baseline shows up as blue, a serious error has occurred. See *Section 3.2.1, Fix Bad Baselines* on page 106 for steps to follow if a baseline fails.

3.1.3 Computing Coordinates

Once the processing is complete, there are two methods to produce coordinates for each station.

Traverse Solution

This solution automatically computes during processing. It starts from known stations and transfers positions to neighboring stations one baseline at a time. A tie or closure will be computed for stations that already have coordinates transferred.

Network Adjustment

This method takes all of the baselines into account into a single weighted least-squares adjustment. It spreads the errors out over the entire network and takes advantage of redundant baselines using covariance weighting to produce more accurate station coordinates. The network adjustment flags erroneous measurements in the sense that the residuals (calculated baseline vector minus observed value) will be unacceptably high. This is most obviously displayed by the PPM (parts per million) value.

How to create a project:

1. Select *GrafNet* from the *Waypoint GPS* program group in your Start menu.
2. Select *File | New Project*.
3. Find the directory where the project files will be located. GrafNet creates many files during processing so using a new directory makes things easier.
4. Give the project a name and click *Save*.

☐ Entering the name of a project that already exists overwrites the file contents.

How to convert data

1. Select *File | Convert | Raw GPS to GPB*.
2. Browse to the directory containing the raw data.
3. Click *Auto Add All* or select the appropriate GPS receiver and convert the data file.

How to add observation files

1. Select *File | Add / Remove Observations*.
2. Click *Get Folder* and select the directory containing the GPB and EPP files.
3. Select the files that you want added.

☐ You only need to select GPB files. The EPP files are assumed to have identical prefix names.

4. Verify the station ID and the antenna height when the dialog box appears.
5. Click the *OK* button.
6. Select *File | Save Project*.

How to add a ground control point

1. Select *File | Add / Remove Control Point*.
2. Click the *Add* button.
3. Select the ID corresponding to the control point to be added.
4. Enter the latitude, longitude and height for that station.

☐ These coordinates should be in the same datum as the selected under *Options | Datum*.

5. Click the *OK* button.

3.2 Start a Project with GrafNet

The information in this section describes how to start a project and quickly process a static network using GrafNet. The individual menu items are discussed later in this chapter.

Install Software

Verify that the installation was successful by ensuring that you have a *Waypoint GPS* program group on your computer. If this program group is not there, see *Section 1.2.2, CD Contents and Installation* on page 12 for installation instructions.

Create a Project

Follow the instructions in the shaded box.

Convert Data

To be processed, raw GNSS data files have to be converted into Waypoint's GPB format. Instructions on how to convert these files are in the shaded box.

Add Observation Files to the Project

Files can be added one at a time by clicking *Add* or all files in the directory can be added by clicking *Select All* followed by *Add*. A dialog box appears requesting verification of the station ID and antenna height. With some receivers this information will be filled in automatically. Always ensure that the ID and antenna heights are correct. Steps on how to add observation files to a project are in the shaded box.

☐ If a station has been observed more than once, the station ID should be the same for each observation. Otherwise, two separate stations will be formed and solved for.

Add a Ground Control Point

Follow the steps in the shaded box to add a ground control point.

Set the Processing Options

Follow the steps in the shaded box to set the processing options.

Process All Sessions

Follow the steps in the shaded box to process all sessions. After these steps are completed, error ellipses on each of the single session baselines and the processing window should both appear.

Verify That All Baselines Have Passed

Passed baselines are plotted in green, failed baselines in red, purple or blue. Duplicate (yellow) baselines do not show the pass / fail via coloring and must be verified. To verify, follow the steps in the shaded box.

If it is a closed loop network and you feel that the solution is correct despite failing GrafNet's statistical tests, right click the baseline and select *Override Status* to override the status. The traverse will transfer coordinates using failed baselines, while the network adjustment will not.

Run Network Adjustment

Follow the steps in the shaded box to run a network adjustment. After these steps are completed, the *Network Adjustment Results* opens, while error ellipses are plotted for each station on the *Map Window*.

Export Station Coordinates

Follow the steps in the shaded box to export station coordinates.

Clean Up processing Files (optional)

Follow the steps in the shaded box to remove some of the intermediate processing files.

How to set the processing options

1. Select the desired static processing mode. These modes are described in *Section 3.1.2, Solution Types* on page 102.
2. Select the desired processing datum.

How to process all sessions

1. Select *Process | Process Sessions*.
2. Select *All unprocessed* as the *Sessions to Process* under the *Process* tab.
3. Click the *Process* button.

How to verify that all baselines have passed

1. Right-click the failed baseline.
2. Select *View Results* or *View Information* to find out where the problem lies.

How to run a network adjustment

1. Select *Process | Network Adjustment*.
2. Click the *Process* button.

How to export a station coordinate

1. Select *Output | Export Wizard*.
2. Enter an output file name.
3. Select the source for the coordinates (usually *Network*).
4. Select a profile containing the desired output variables.

How to clean up processing files

1. Select *File | Remove Processing Files*.

How to fix bad baselines

Fixed Static Solutions

If fixed solution fails, then try to switch to a float solution. Remember that float solutions are not very good at achieving centimeter accuracies unless there are many hours of data.

Forward / Reverse Processing

Switch from Forward to Reverse processing. The reverse solution might pick a different base satellite and have a different solution that passes. GrafNet will pick the forward or reverse solution with the latest date so reprocess the forward solution if the reverse is unacceptable.

Changing the Elevation Mask

GrafNet by default uses a 15° elevation mask. This is because tropospheric and ionospheric errors increase significantly on low satellites. Lowering the mask to 10° allows more satellites into the solution, strengthening the geometry. This improvement might offset the atmospheric errors.

Use ARTK

Use ARTK in GrafNav for an individual baseline. Edit with GrafNav and then reprocess with GrafNav by enabling ARTK and engaging ARTK in static mode.

Start and End Times

The start / end times can be modified from within the *General* tab. Sometimes a data set can have parts that are unusable. A good indicator is the *L1 Phase RMS* plot. Entering the start and end times eliminates these parts by selecting the appropriate times. Another way to find good sections of data is to view the FSS or RSS files. There is a section at the start showing numerous periods of cycle slip free data for various satellites and it also shows which period was used. You can also try entering the start / end times from another period exclusive to the one used.

Doppler Usage

Bad Doppler data sometimes makes data process poorly. Detect this by plotting the L1 Doppler RMS. If there are any large spikes (5 or more times the size of the Doppler standard deviation), then this data may have problems. Try shutting the Doppler OFF for carrier phase processing from within the *Advanced* options.

Satellite Omission

A bad satellite has many bad data warnings in the message log file (FML/RML). Omit this satellite with the *Advanced* tab options.

Continued in the shaded box, on the following page.

3.2.1 Fix Bad Baselines

Some baselines appear red when running GrafNet and duplicated baselines appear yellow. When examining the baseline sessions from within the *Sessions* window of the *Data Manager*, one or more sessions will have *Bad* indicators. This means that one or more tests have failed in the static solution. If a baseline is flagged as *Approximate*, then the baseline was only able to achieve an approximate (1-5 m) solution and it has failed. These baselines can also be considered *Bad*.

The purpose of this section is to help you re-process these baselines to achieve better results. There are many causes of a failed baseline, and not every solution is given. In some cases, the correct solution has been found, but the statistics just fail. This indicates that GrafNet cannot label this baseline as correct. If there are loops that are closed in this solution, then you can change the status from *Bad* to *Good* using *Override Status* from within the *Sessions* window of the *Data Manager*.

The shaded boxes on this page and the following page contain optional approaches to fix bad data.

3.2.2 Unfixable Data

Sometimes data is simply bad and changing the options cannot help. This section discusses some of the possible causes of such data in the shaded box. For some cases, there is advice for improving the solution.

How to fix bad baselines continued...

Measurement Standard Deviations

For a float or iono-free solution, changing the standard deviations for both the L1 carrier phase and the C/A code improves a solution. Obtain suitable standard deviations by viewing the plots for both the C/A code RMS and the L1 phase RMS. A good standard deviation value is one in which about 90% of the RMS values fall below. Realistic values allow the Kalman filter to perform better.

About unfixable data

Moving Antenna

An antenna that is not still causes havoc with static processing. This can be caused by an operator not holding the antenna still, heavy winds or a vehicle that is rocking. Theoretically, this data should be processed as kinematic and the position solutions averaged. However, GrafNet does not currently support this mode of processing so this data should be avoided. If it needs to be processed, a float solution will perform best.

Ionospheric Effect

Heavy ionospheric activity can cause large carrier phase noise. A single frequency receiver cannot do much to alleviate the problem. However, dual frequency data will most likely process better with an iono-free solution rather than some of the fixed integer techniques, such as the fixed solution.

Constant Loss of Lock

Antennas placed under trees or similar obstructions will often continuously lose lock, which causes the fixed static to fail and the float solution to report poor accuracy.

Poor Antenna Location

High multi-path mostly affects the C/A code but the carrier phase can also be affected and might cause a fixed solution to fail. Antennas placed near large metal structures are most affected. Locations on rooftops can also cause poor data. Avoid these locations. The only suggestion for possibly improving this data during processing is to reduce the size of the C/A code standard deviation from within the *Measurement* tab of the processing options.

Receiver Problems

Sometimes a GPS receiver just collects bad data. Low power or a poor antenna connection can cause this. If the problem is consistent with a particular GPS receiver unit, have the manufacturer check the GPS receiver.

How to open a project

1. Select *Open Project* from the *File* menu.
2. Choose the name of the project from the dialog box that appears prompting you to select the name of an existing project (GNT file).
3. Click the *Open* button.

3.3 File

3.3.1 New Project

To process a network for the first time, you must start a new project. This is done via *File | New Project*. GrafNet's project configuration files carry a GNT extension.

3.3.2 Open Project

To open an existing project, follow the steps in the shaded box.

3.3.3 Save Project

The program automatically saves the project file (GNT), *Session Report* (REP) and *Traverse Solution* (TRV) files before processing. Any changes made to the observations like name or antenna height are also saved.

3.3.4 Save As

Use the *Save As* command under the *File* menu to create a new project that has identical processing options as the current project. This allows you to change the options in the new project and process the data without losing the solution computed by the original configuration.

3.3.5 Print

This option allows you to print different windows.

3.3.6 Add / Remove Observations

This feature adds observation files to GrafNet projects. These files must be converted to GPB files using *File | Convert | Raw GNSS to GPB*.

GrafNet extracts the station name and antenna height values from the STA file, which is created during the conversion process.

Station Name and Antenna Height

Verify that these values are correct and disable the option *Prompt for station name and antenna height* to add observations without user input. Double-check *station names* and *antenna heights* in the *Observations in Project* list. Correct errors by right-clicking the observation and selecting *Edit*.

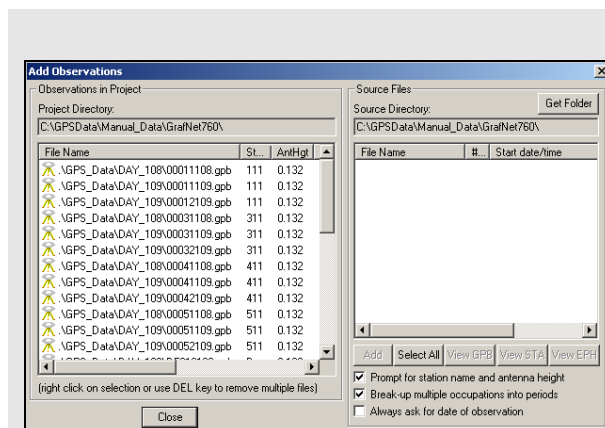
Antenna Profiles

GrafNet lets you select an antenna profile. Because additional offsets to the L1 and L2 phase centers are added, when using profiles other than *Generic*, match up the antenna height measurement to the expected measuring mark on the antenna. See *Section 2.3.6, Add Master File(s)* on page 21 for help. If a slant measurement is selected, then a correction is applied based upon the size of the antenna ground plane. Be sure that the origin, known as the measuring mark, is defined.

Observation Files

Adding observations breaks observation files into multiple periods if a gap of 3 minutes or more is detected. This is controlled with *Break-up multiple occupations into periods*. Some RINEX files have gaps but are observed over the same point for the entire observation period so disable this option. For cases where the time gap is very short because the station-to-station movement is very fast, control the minimum time gap for breaking up periods with the *Solution and Session* tab under *Options | Global Settings*. Look for the Minimum time span for breaking up observations into periods.

-
- ☒ Station IDs must match those of all observations for a given station and those of matching ground control points. Reprocess sessions associated with an observation if the antenna height has been changed. This is performed by right-clicking on the station for that observation and selecting *Remove Processing Files*. Then, select *Reprocess entire project* under *Process | Process Sessions*.
-



Add/Edit/Remove Control Points

List of Points:

Name	Type	Latitude	Longitude	Height
nji2	3-D	40 44 29.3...	-74 10 39.727...	17.930

(These coordinates are in processing datum and height above ellipsoid)

Close Add Edit Remove

Add/Edit/Remove Check Points

List of Points:

Name	Type	Latitude	Longitude	Height
NJTR	3-D	40 15 27.4...	-74 47 48.072...	41.295

(These coordinates are in processing datum and height above ellipsoid)

Close Add Edit Remove

- ✉ The latitude and longitude coordinates should be in the same datum as the selected datum. The height can be entered as meters above the ellipsoid or mean sea level. If height above mean sea level is used, you have to select a geoid file. If a mean sea level, or orthometric, height is entered here, then only an approximate geoid correction is applied. As stations become more distant from the control point, orthometric height errors will increase. If more than one control point is present, and orthometric heights are entered, the height ties may be poorer as well.

3.3.7 Add / Remove Control Points

Add at least one horizontal ground control point before processing. Sessions will not be processed unless they are connected to a control point. The three types of control points include the following:

- 3D: constrained horizontally and vertically
- 2D: constrained horizontally
- 1D: constrained vertically

After selecting *Add / Remove Control Points* from the *File* menu, click *Add* to enter a new control point or *Edit* to adjust the station, position or Datum of a control point. The station ID should match that of the corresponding station.

Standard deviations can be entered at this stage. The default values are 5 mm for horizontal and 5 mm for vertical. You can change them to more realistic values. Standard deviations are only taken into account in the network adjustment. They are useful for combining high and low accuracy control points.

3.3.8 Add / Remove Check Points

Check points are useful for gauging how well the network fits the existing control fabric. They are added in the same manner as control points, except that standard deviations cannot be defined. It is important that the processing datum matches the coordinates' datum.

3.3.9 Alternate Ephemeris / Correction Files

Adds additional precise or broadcast ephemeris files (SP3 / SP3c and EPP files). See *Section 2.3.8, Add Precise Files* on page 23 for more information.

- ✉ Be sure that the entire span is covered.

3.3.10 Remove Processing Files

This feature can be used to clean up a directory by removing the session-dependent files. Solutions for static sessions are stored in the FSS for forward and RSS for reverse processed files. The FWD / REV and FML / RML files are unnecessary and can be removed. Selecting *All Files* removes all files including the solution files. You must reprocess for further analysis. See *Section 2.3.12, Remove Processing Files* on page 33 for details.

3.3.11 Import Project Files

This feature does the following:

- Reads all configuration file settings from the selected CFG.
- Copies the processing files associated with the CFG.
- Loads the new solution into memory.

3.3.12 View

ASCII File

See *Section 2.4.8, ASCII File(s)* on page 41 for information regarding this feature.

Raw GPS Data

See *Section 2.4.9, Raw GNSS* on page 41 for information regarding this feature.

3.3.13 Convert

The two conversion utilities that are available with this option are listed in the shaded box.

3.3.14 GPB Utilities

A number of utilities are available for use with GPB files. See *Chapter 5, Utilities* on page 141 for information regarding any of these utilities.

3.3.15 Recent projects

Displays recent projects.

3.3.16 Exit

Exits the program.

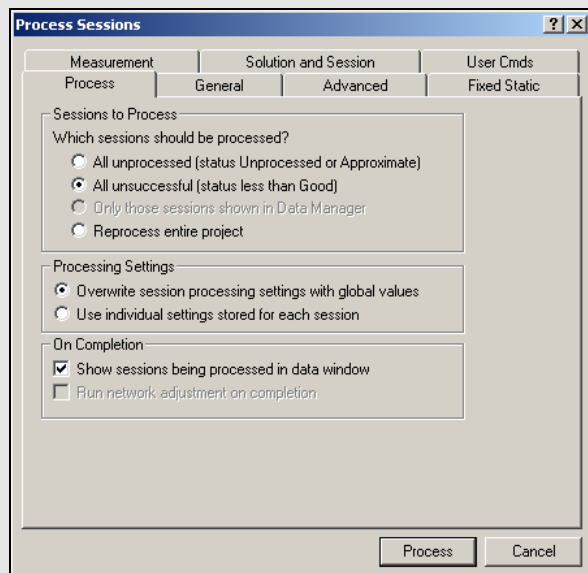
Two conversion utilities available with *File | Convert*

Raw GNSS to GPB

Users have to convert their raw data files to GPB format in order to process them with the software. More information on this utility is available in *Chapter 5, Utilities* on page 141.

GPB to RINEX

Users who wish to produce a RINEX file from their GPB files may do so using this utility. This utility supports the creation of Version 2.0 and 2.1 of the RINEX format. For additional information, see *Chapter 4, File Formats* on page 131.



Sessions to process

All unprocessed

Processes all sessions listed as either *Unprocessed* or *Approximate*. These sessions are blue or purple in *Map Window*.

All unsuccessful

Processes all sessions that do not have a *Good* status. This includes all sessions that are not green in the *Map Window*. Processing will start nearest to the control points and move outward. For processing problem sessions, it may be better to process through GrafNav.

Only those session shown in Data Manager

Process only the sessions that are presently listed in the *Data Manager* window.

Reprocess entire project

Reprocesses all solutions, regardless of status. It is a good idea to reprocess all sessions after changing the global options.

Processing settings

Overwrite session processing settings with global values

Applies the options set under *Options | Global Settings* to all baselines being processed. Any individual baselines whose settings were changed will have their settings overwritten.

Use individual settings stored for each session.

Uses the options as individually set for each baseline for processing.

3.4 Process Menu

3.4.1 Processing Sessions

This option brings up the *Process Sessions* window, where a number of options pertaining to processing are available.

Process

Sessions to Process

Allows you to decide which session to process. The options are listed in the shaded box.

Processing Settings

Determines which processing settings to use for each baseline. The options are listed in the shaded box.

On Completion

Defines actions to be taken when processing is completed. The following two settings are available:

Show sessions being processed in data window

Displays all processed sessions in the *Data Manager* window.

Run network adjustment on completion

Will automatically bring up the *Network Adjustment* window. See *Section 3.4.6, Network Adjustment* on page 118 for more information.

General Options

Process Direction

The direction can be set to *Forward*, *Reverse* or *Both directions*. GrafNet uses the most recently created solution file. The forward and reverse solution should provide roughly the same solution but in some circumstances, a reverse solution passes when a forward has failed, or solutions may differ because of different base satellite selections. If both directions are selected, the combination of the two solutions will be used. See *Section 2.5.2, Combine Solutions* on page 56 for more information.

Static Solution Type

See *Table 11, Solution Types* on page 102 for information.

Frequency

Defines the type of data used for processing. The following settings are available:

Single frequency

Forces single frequency (L1 only) processing

Dual frequency

Forces dual frequency processing. L1 / L2 data must be present in all observation files.

Automatic

Auto-detects single or dual frequency processing for each baseline. This is the default mode and should be used under most circumstances.

GPS / GLONASS Mode

Applies to data logged using GLONASS-enabled receivers. The following settings are available:

Automatic

Enables the use of GLONASS data.

GPS only

Disables GLONASS processing. This option may be useful if GLONASS data is causing problems.

GPS+GLONASS

Forces the use of available GLONASS data. Should be used if automatic detection fails.

Elevation Mask

Satellites below this mask angle will be ignored. The default value is 15°. Lowering this value allows more satellites to be used, possibly improving a solution with poor geometry.

Time Range

This option is only available for individual baselines by right-clicking on the session in the *Data Manager* and selecting *Options*.

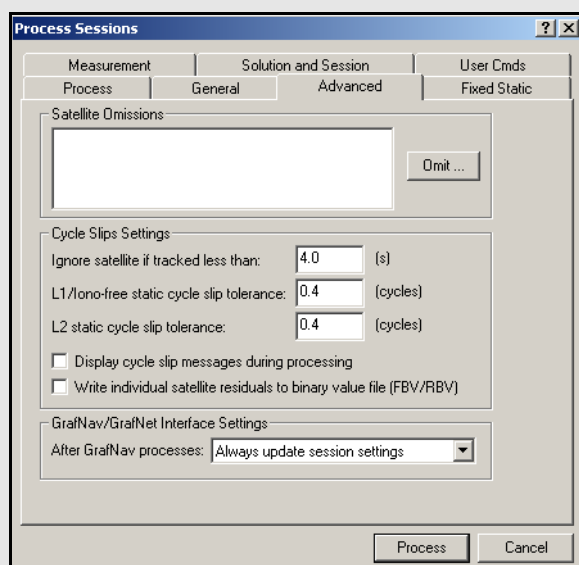
Interval

Allows you to choose the processing interval. The default interval is the interval at which the data was logged. If the logged data rate is high (1 Hz), override this interval with 15 seconds. Processing static data at intervals shorter than 15 seconds is not beneficial, will not improve accuracies and could result in overly optimistic accuracy estimates due to the high time correlation of carrier phase data.

Table 12: Processing Modes

Mode	Freq.	Minimum Observation Time (min)	Maximum Distance (km)	Approximate Accuracy
Fixed	Single Dual	15 5	15 50	5mm + 1ppm 5mm + 1ppm
Float	Single	See Note 2	See Note 3	10mm + 2ppm
Iono-free	Dual	See Note 2	See Note 3	10mm + 0.5ppm
Auto	Single Dual	Chooses between Fixed and Float depending on baseline distance. Chooses between Fixed and Iono-free depending on baseline distance.		

- ✉ 1. Observation times should be increased for longer baselines. For single frequency, a good rule of thumb is 10 min + 1 min / km. For dual frequency, these times can be halved. Observation times should also be increased during times of poor satellite geometries that is, high PDOP.
2. No minimum time is given, but accuracy improves with observed time. A few minutes of observation will only achieve sub-metre accuracies under very good operating conditions.
3. For dual frequency receivers, use fixed or float solutions for baselines less than 50 km, and iono-free solutions for more than 50 km.
4. Accuracies are given for average occupation time. Accuracies increase for longer times and degrade with poor geometry or bad measurement quality.
5. Use precise ephemeris for baselines longer than 150 km. See *Section 3.3.9, Alternate Ephemeris / Correction Files* on page 110 for information.



Cycle slip settings

Ignore satellite if tracked less than

Specifies the number of seconds of continuous carrier phase lock before data for that channel is deemed usable. This allows you to reject data for the first n seconds after acquiring lock. The default value is 4, but higher numbers (8 to 12 seconds) can be very beneficial to some GNSS receivers, especially low-cost ones.

L1 / Iono-free static cycle slip tolerance

Controls cycle slip detection in static mode. You may have to raise this if you are processing extremely noisy carrier phase data. In static mode, the fine static check is turned on by default, allowing GrafNet to detect very small cycle slips. For fixed solutions, this is automatically used and cycle slips are also corrected. Cycle slip corrections for fixed solutions can be disabled from the Fixed Static options tab.

L2 static cycle slip tolerance

During ARTK and relative ionospheric processing, GrafNet checks for small cycle slips on L2 by comparing it against the L1 phase. Raising this value too high increases the chance of detecting a half cycle slip. Lowering this value might cause false cycle slips to be induced from noise. Only advanced users should change this value since it requires an analysis of the results.

Display cycle slip messages during processing

Prints satellite cycle slips and rising/falling messages to the FML and RML files. Disabling this option creates a more concise message log but these messages might help identify a bad satellite.

Write individual satellite residuals to binary value file

Writes carrier phase and code residuals for each satellite and baseline to FBV and RBV files. Required in order to view the individual satellite value plots.

Advanced Options

Satellite Omissions

See *Satellite / Baseline Omissions* in the *Advanced Tab* on page 45 for more information.

Cycle Slip Settings

The settings are listed in the shaded box.

GrafNav / GrafNet Interface Settings

If you export baselines to GrafNav, the options below are available to specify how changes made to the processing settings in GrafNav affect those in GrafNet.

- ☒ If you decide to have the processing settings in GrafNet updated to match those used in GrafNav, they will only be stored for the individual baseline that was exported. The global processing options for the GrafNet project are unaffected.

Always update session settings

Any changes made to the processing settings in GrafNav will be saved to that baseline's processing settings in GrafNet.

Never update

Any changes made in GrafNav will not be saved in GrafNet. As such, GrafNet will retain the settings that were used at the time of export.

Prompt user before update

You will be prompted after every processing run in GrafNav as to whether or not the processing settings used should be saved to GrafNet.

Fixed Static Options

See *Fixed Static* on page 54 for information regarding all the settings on this tab.

Measurement Options

See *Measurement* on page 50 for information regarding all the settings on this tab.

Solution and Session Options

Forward / Reverse Process Direction Handling

Allows you to change the way forward and reverse solutions are chosen for use in the network. By default, GrafNet will load the latest solution (most recently processed). However, if you want to use a combined solution, select the *Automatically combine FWD / REV solutions* option.

Session Forming Options

The two settings available are listed in the shaded box.

Distance Tolerance for Using Fixed Over Float

This tolerance is used when you select *Automatic* for the *Static Solution Type* under the *General* tab. If the baseline distance is longer than the tolerance, then a float solution will be used for single frequency, while an iono-free solution will be used for dual frequency. Otherwise, the fixed static solution is used.

User Command Options

See *User Cmds* on page 55 for more information on this tab. The list of available commands can be found in *Appendix C, Summary of Commands* on page 177.

3.4.2 Rescanning Solution Files

This option rescans the FSS (forward static solution) or RSS (reverse static solution) files. When deciding between the forward or reverse, it will use the one most recently created. Under normal circumstances, solution scanning is automatic, but there are a few instances when you may want to rescan manually, such as when using GrafNav in conjunction with GrafNet.

The screenshot shows the 'Process Sessions' dialog box with the 'Solution and Session' tab selected. The 'Forward/Reverse Process Direction Handling' section has two radio buttons: 'Use FWD/REV solution last processed' and 'Automatically combine FWD/REV solutions' (which is selected). Below this is a note: 'Will either use best solution or statistical combination'. The 'Session Forming Options' section, which is highlighted with a shaded box, contains two input fields: 'Minimum observation time for forming a session:' set to 180.0 (seconds) and 'Minimum time span for breaking up observations into periods:' set to 180.0 (seconds). The 'Distance Tolerance for Using Fixed over Float' section has two input fields: 'Single Frequency:' set to 10.00 (km) and 'Dual Frequency:' set to 40.00 (km). At the bottom of this section is a checkbox labeled 'Revert to Float solution if Fixed or Quick Static fails'. The dialog has 'Process' and 'Cancel' buttons at the bottom right.

Session Forming Options

Minimum observation time for forming a session

Controls the minimum number of seconds necessary to declare concurrent observation files as a session. The default value is three minutes. For dual frequency data, this time can be reduced, while for single frequency data, this value may have to be lengthened to avoid short / low accuracy baselines.

Minimum time span for breaking up observations into periods

Controls the time required between sessions in order to have them recognized as two separate sessions. The default is three minutes. This gets used when observations are added to the project with the *Break-up multiple occupations into periods* option enabled in the *Add Observations* window. See *Section 3.3.6, Add / Remove Observations* on page 109 for more information.

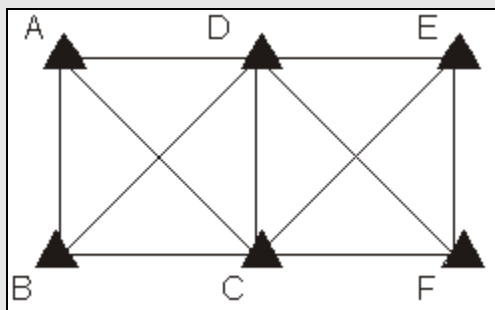


Figure 3: Trivial Baselines

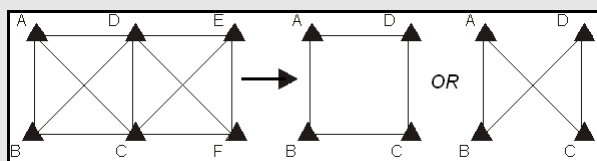


Figure 4: Removal of Trivial Baselines

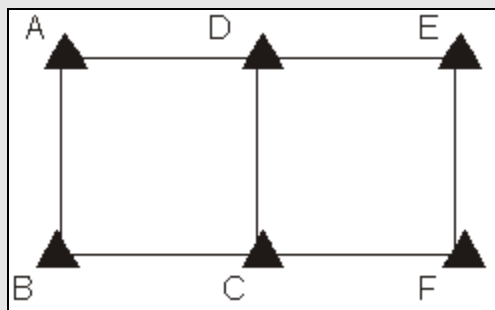


Figure 5: Network with Trivial Baselines Removed

3.4.3 Ignore Trivial Sessions

GrafNet defines trivial baselines as those that are unnecessary and result from multiple receivers simultaneously running. The problem with this is that the baseline solutions computed by GrafNet are correlated, and so they are dependent. Removing trivial baselines reduces these dependencies, while still maintaining a closed loop. It also creates a network where the standard deviations reflect the actual errors more accurately.

Consider the network in *Figure 3, Trivial Baselines*. The six stations are surveyed with four receivers during two one-hour sessions. During the first session, stations A, B, C, and D are observed. During the second session, the points C, D, E, and F are observed.

This network can be divided in two sub-networks, formed by the first and second time periods. Before the trivial baseline removal, every baseline in these two sub-networks is dependent on the other baselines. These dependencies cause the loop ties to be low.

With four receivers or more collecting data at the same time, a sub-network is very over-determined. Using three GPS receivers, the network is still over-determined, but all baselines need to be included to form a closed loop. GrafNet removes these dependent or trivial baselines by creating a single loop that connects all of the points in the sub-network. *Figure 5, Network with Trivial Baselines Removed* illustrates that it is easy to remove these baselines.

With four receivers, there are two dependent baselines in each sub-network. GrafNet removes these trivial baselines for each sub-network. *Figure 4, Removal of Trivial Baselines* shows two possibilities of what GrafNet might do with the first sub-network.

GrafNet removes the trivial baseline by setting their session status to *Ignore*. It is possible to un-ignore any session by simply changing its status back to *Unprocessed*. GrafNet tries to keep the sessions that are of best quality. The following criteria is considered:

- The amount of time the baseline was surveyed.
- The frequencies used in the surveying of the session.
- The length of the baseline.
- The number of connecting baselines to the two end-points.

As shown in *Figure 5, Network with Trivial Baselines Removed*, GrafNet automatically excluded AC, BD, CE, and DF. It then forms a single loop for each of the time periods. DC is a baseline with a duplicate session.

3.4.4 Unignore All Sessions

This feature changes the status of all ignored sessions from *Ignore* to the status they had previously.

3.4.5 Compute Loop Ties

In some cases, the Traverse or Network residuals show a poor fit. The first step is to ensure that the network is minimally constrained, which means that there should only be one 3-D control point, or one horizontal and one vertical point. Convert any additional control points to check points. See *Section 3.3.8, Add / Remove Check Points* on page 110 or *Section 3.6.5, Show Data Window* on page 124 for help.

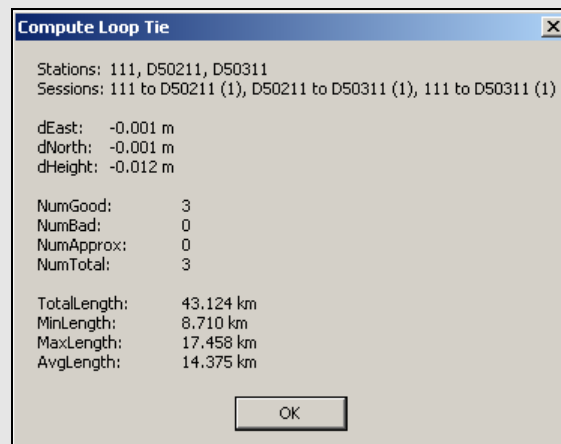
For a constrained network, the poor fit indicated by large residuals can be caused by the following two issues:

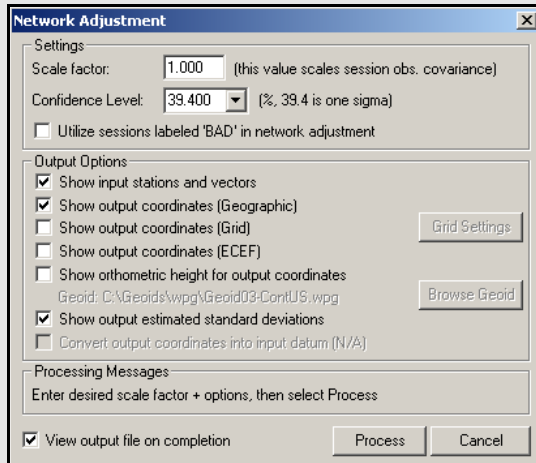
- Incorrect antenna heights used for multiple occupations of a point
- Baseline solution is incorrect (by far the most common cause)

In some cases, it is obvious from the traverse output which baseline is the culprit, but often further investigation is required. The Compute Loop Tie feature makes such examinations much easier. By adding the vectors of a loop within the network, discrepancy values are formed in the east, north and height directions. For a loop without problems, these values should be near zero. If not, then one of the baselines forming the loop has an error. Loops can be formed in the following two ways:

- Selecting stations of vertices
- Selecting baselines forming legs of loop

Make the selections on the map or select the stations or sessions in the *Data Manager* window. After selecting the first station or session, hold down the *Ctrl* key while selecting the remaining ones. Selection must be continuous, but it does not matter if the loop is formed in the clockwise or counter-clockwise direction. Once a complete loop is formed, select *Process | Compute Loop Tie* or right-click on one of the selections in the *Data Manager* window and select *Compute Loop Tie*. A window containing various statistics for the closed loop is displayed.





How to process with the Network Adjustment

1. After successfully processing all of the baselines within GrafNet, access the network adjustment via *Process | Network Adjustment*.

✉ The network adjustment only accepts session data flagged as *Good*. Other baselines will be ignored unless otherwise specified with the *Utilize sessions labeled 'BAD' in network adjustment* option.

For the initial few runs of the network adjustment, the scale factor should be set to 1.0. This will not scale the final standard deviations to match observed session vector residuals. See *Variance factor* on page 120 for more information.

2. Click the *Process* button to compute a network adjustment solution. Any errors encountered are displayed.
3. If there are any “hanging stations”, which are stations that are not attached to the network or are attached by a *Bad* baseline, the adjustment will fail. It is possible to change the status of the baseline to *Good* from the *Sessions* window in *Data Manager*.
4. A .net file is created, which can viewed via *Process | View Network Adjustment Results*.

✉ The network adjustment must be re-run if you have reprocessed sessions or changed the station configuration.

3.4.6 Network Adjustment

This option invokes the network adjustment contained within GrafNet. External network adjustment programs, such as GeoLab, also support GrafNet's output format.

The network adjustment is only available within GrafNet. It is a means to more accurately compute each station's coordinates given the solution vectors computed for each session / baseline. Such an adjustment uses the X, Y and Z vector components and also utilizes the 3 x 3 covariance matrix which is the standard deviation values + coordinate-to-coordinate correlation. Using least squares, the errors are distributed based on a session's estimated accuracy. More weight is placed on sessions with lower standard deviations.

Advantages

In the traverse solution, each station's coordinates are determined using one session from one previous station. For networks with redundant measurements, which is usually the case, this can lead to a sub-optimal or even erroneous determination of a station's coordinates. The network adjustment does a much better job of distributing errors than the traverse solution. This makes it less sensitive to errors as long as a session's estimated accuracy is representative of actual errors. Thus, the network adjustment generally produces more accurate station coordinates.

Another advantage of the network adjustment over the traverse solution is that it assigns a standard deviation to each point. Estimated standard deviations should be used with caution, but they are a good tool for locating outliers. See *Section 3.4.2, Rescanning Solution Files* on page 115 for more information on scaling standard deviations to match the data accuracy.

Before running the network adjustment, all baselines must have already been processed. Only good (green) baselines will be used, unless otherwise specified with the *Utilize sessions labeled 'BAD' in network adjustment* option.

Settings

Scale Factor

Error ellipses should appear on the stations in the *Map Window*. These ellipses are scaled by this option.

Confidence Level

The level of confidence (in percent) of the error ellipse can also be adjusted. This uses a statistical 2-D normal distribution. Changing this value does not alter the final coordinates, but it will scale the final standard deviations and covariance values. For example, 95% results in a standard deviation scale factor of 2.44.

Output Options

Controls what is output from the network solution.

Show input stations and vectors

Outputs all the control and check points and their vectors. The coordinates are output in geographic form.

Show orthometric height for output coordinates

Requires that you provide a geoid file, which can be selected with the *Browse Geoid* button.

Other output options include outputting the estimated standard deviations.

To process the network adjustment, click the *Process* button. This step must be performed each time a project is re-loaded.

View output file on completion

Lets you view the ASCII solution file once the adjustment has been made.

Using Multiple Control Points

When multiple control points are present, it is important to initially use only one. This prevents errors in the existing control from causing otherwise correct session vectors not to fit. Therefore, large tie errors in the traverse solution or large residuals in the network adjustment are attributed to GPS errors.

The variance factor is only truly valid as a scale factor for a minimally constrained adjustment. See the shaded box for information about interpreting the output. Once satisfied with the quality of the GPS data and the fit of the session vectors, you can add additional control points with *File | Add / remove Control Points* or by right-clicking on a station in the *Map Window* and selecting *Add as Control Point*.

Since the network adjustment is a least-squares adjustment, it attempts to move control point coordinates to make the network fit better. This is an undesirable effect for many applications. To avoid it, give control points very low standard deviations. The default value is 5 mm, which might have to be lowered if the network fit is poor. Lowering the standard deviation to 0.0001 m forces the control point to “stay put”. A standard deviation of zero is not allowed. Change the standard deviation for control points via *File | Add and Remove Control Points*. Select the desired control point and click *Edit*.

How to interpret the output

The network adjustment output is an ASCII file that can be printed from GrafNet.

Input Stations

This is a list of the control (GCP) and check (CHK) points in the project. Their associated geographic coordinates and standard deviations are also shown.

Input Vectors

This is the ECEF vector components for each session that has a *Good* status. The lower triangular of the ECEF covariance matrix is shown next to the vector components. The value in brackets is the standard deviation of the ECEF X, Y or Z axis in meters. The covariance values are not scaled by the Scale Factor entered at the start.

Output Vector Residuals

This is the most important section of the network adjustment output. It indicates how well the session vectors fit in the network. The residual values are shown in local level, where RE is the east axis residual, RN is the north axis residual and RH is the Z axis residual. These values are expressed in metres and should ideally be a few centimeters or less. Larger values may be acceptable for larger networks.

In addition to the residual values, a parts-per-million (PPM) value is shown. This indicates the size of the residuals as a function of distance. 1 PPM corresponds to a 1 cm error at a distance of 10 km. The baseline length is also shown in kilometers. Baselines less than 1 km can have large PPM values. This is because other errors such as antenna centering become an influencing issue. This might not indicate an erroneous session solution. The last value is the combined (east, north and up) standard deviation (STD). This indicates sessions that have one or a combination of the following:

- float solution
- poor satellite geometry (that is, high PDOP)
- short occupations

Check Point Residuals

If check points have been added, this section shows how well the known coordinates compare to those computed by the network adjustment.

How to interpret the output cont.

Control Point Residuals

This section shows the adjustment made to control point residuals. When just one control point is used, then the adjustment will always be zero. With two or more points, the adjustment depends on the input control point standard deviation and the session vector standard deviations.

Output Station Coordinates

This shows the computed coordinates for each of the stations both in geographic and ECEF coordinate systems. The output datum is indicated by the *Datum* parameter at the top of this file.

-
- ☒ The geographic height should be ellipsoidal.
However, this is only true if you enter an ellipsoidal height for the control point elevation.
-

Output Variance / Covariance

This section shows the local level (SE, SN and SZ) standard deviations along with ECEF covariance values. The standard deviation values are scaled by both the input scale factor and the statistical (confidence) scale factor. The covariance values are only scaled by the input scale factor. If error ellipse parameters are desired, then the *Write Coordinates* feature should be used.

Variance factor

See *Variance Factor and Input Scale Factor* on page 120 for information.

Using Horizontal and Vertical Controls

GrafNet supports horizontal and vertical control points in addition to full 3-D control. To utilize this control, you must have available 1-10 m accurate coordinates for the unknown axes (that is, Z for horizontal points and latitude and longitude for vertical points). These coordinates can be obtained from the single point solution (in the absence of SA) or from an initial network adjustment run using just one 3-D control point. The latter method is normally used.

When the vertical and horizontal control points are added, it is important to de-weight the unknown axes. For vertical control points, the horizontal standard deviation is set to 100+ m. For horizontal control points, the vertical standard deviation is set to 100+ m.

Obtain Orthometric Heights

Orthometric heights are available in the network adjustment output.

Variance Factor and Input Scale Factor

The variance factor is at the bottom of the network adjustment output. It is the ratio between the observed residuals errors and the estimated session (baseline) accuracies. Ideally, the variance factor should be 1.0. This indicates that the estimated errors correspond well to observed errors. A variance factor less than 1.0 indicates that the estimated errors are larger than the observed errors (that is, session standard deviations are pessimistic). Most often, a value greater than 1.0 denotes that observed errors are larger than estimated accuracies (that is, session standard deviations are optimistic) exists unless the GPS data is very clean. Thus, low variance factors are normally desired. Very large variance factors of 100+ normally indicate abnormally large session errors (that is, a very poor network fit), and you should try and investigate the source of the problem before using the coordinates produced.

The variance factor can also be used to scale the station standard deviations to more realistic values. The network adjustment is initially run with a unity scale factor. The resulting variance factor can then be inserted in the scale factor field from the first screen. After running the network adjustment with this new scale factor, you will notice larger or smaller standard deviations and that the new variance factor should now be ~1.0. This procedure will only work for a minimally constrained adjustment (that is, one 3-D control point, or one 2-D and one 1-D control point).

3.4.7 View Traverse Solution

GrafNet computes a traverse solution automatically after processing each session. This feature can be used to view traverse solution files (TRV).

Traverse Solution

Once all of the baselines have been successfully processed, meaning that they are green in the *Map Window*, you can produce coordinates for each of the stations. Do this using the traverse technique from known station to unknown stations. Using *File | Add / remove Control Points*, additional known (fixed) control points can be specified.

At least one GCP is needed per project before GrafNet will process any data, but others can be added later. These known control stations are used to transfer coordinates to unknown stations in the network.

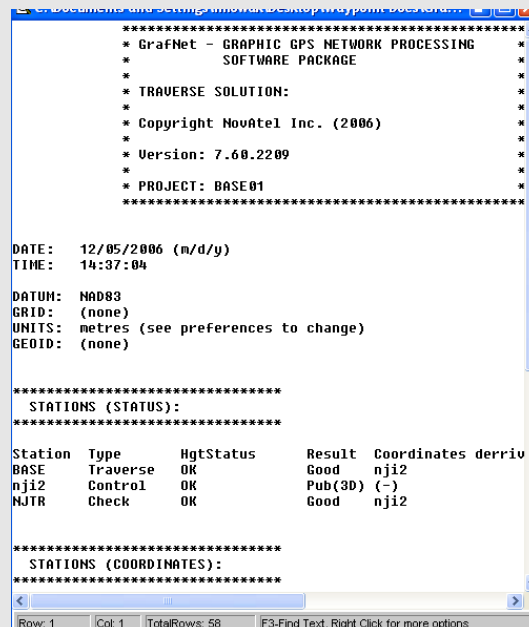
In some ways, this is very similar to a conventional traverse survey but instead of instrument, backsight and foresight stations, this traverse technique only has an instrument and foresight station. Starting from the known stations, coordinates are transferred to the nearest stations. Then, the next nearest stations receive coordinates. This procedure is repeated until all connected stations have coordinates transferred. The arrow marker on the baseline shows in which direction this transfer takes place.

The coordinates for a given station are transferred from the minimum number of legs. The lengths of the legs are not taken into account which, in some cases, results in an unfavorable transfer of position. In this case, the network adjustment produces more accurate coordinates.

For stations that have more than two baselines connecting, a loop tie can be computed. This means that there is more than one possible transfer of coordinates to this point. The first transfer is used for coordinate generation. Subsequent transfers are used to compute loop ties. The loop ties are good for locating erroneous baselines but they are an accumulated error of many baselines to that point. This means that the last baseline in that traverse leg may not be the erroneous one. These ties also give a good indication of the accuracy of the network, but the magnitude of the errors will be larger than the network adjustment residuals. The network adjustment method is not that much more accurate than the traverse method. Rather, the traverse method accumulates errors (closures) while the network adjustment spreads these errors across the whole network.

3.4.8 View Processing Report

This option displays the RPT file containing information about the stations, sessions, baselines and observations. It also gives a summary for each session processed.



```

*****
* GrafNet - GRAPHIC GPS NETWORK PROCESSING
* SOFTWARE PACKAGE
*
* TRAVERSE SOLUTION:
*
* Copyright NovAtel Inc. (2006)
*
* Version: 7.60.2209
*
* PROJECT: BASE01
*****

DATE: 12/05/2006 (m/d/y)
TIME: 14:37:04

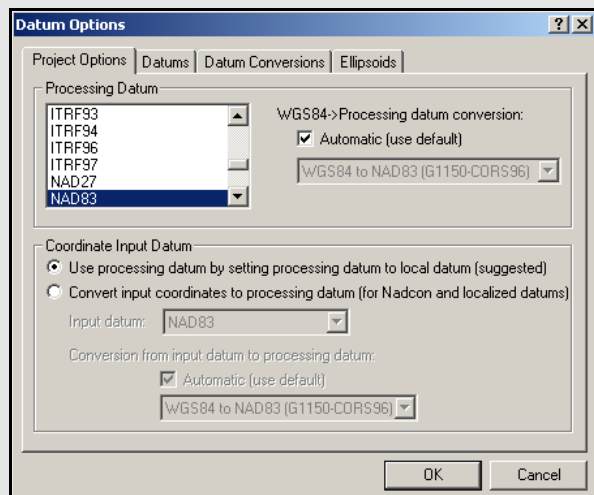
DATUM: NAD83
GRID: (none)
UNITS: metres (see preferences to change)
GEOID: (none)

*****
STATIONS (STATUS):
*****

Station Type HgtStatus Result Coordinates
BASE Traverse OK Good nj12
nj12 Control OK Pub(3D) (-)
NJTR Check OK Good nj12

*****
STATIONS (COORDINATES):
*****

```



3.4.9 View All Sessions

View the *Session* window of the *Data Manager* for all baselines with this feature. It can also be invoked for individual sessions by clicking on a baseline in the *Map Window*. This is a useful way of ensuring all sessions have a *Good* status.

3.4.10 View All Observations

This option displays information about each observation in the *Data Manager*. Right-click on the observations and select *View* to bring up a message box that shows the file name, station name, antenna height, time range and data interval, among other things. Selecting *View GPB File* will access the *GPB Viewer*.

3.4.11 View All Stations

This feature displays the *Stations* window in the *Data Manager*. This window lists all stations in the project, as well as their traverse solution coordinates.

3.5 Options Menu

3.5.1 Global Settings

This feature accesses the global processing options. The options set here are applied to all baselines in the project, overriding any settings that may have been customized for individual baselines. The processing settings for individual sessions can be customized by right-clicking on the session in the *Data Manager* and selecting *Options*.

3.5.2 Sessions Settings (Shown in Data Manager)

This feature allows you to set the processing options for only the sessions currently appearing in the *Data Manager*. In order to use this feature, the *Sessions* window of the *Data Manager* must be open.

3.5.3 Datum Options

See *Section 2.6.3, Datum* on page 58 for help with this feature.

3.5.4 Grid Options

See *Section 2.8.7, Grid/Map Projection* on page 87 for information regarding this feature.

3.5.5 Geoid Options

This feature lets you select the geoid for the project. The geoid selected is used as a reference when outputting orthometric heights in the *Traverse Solution* (TRV) file. It is also used as a default for orthometric height output when running the network adjustment.

3.5.6 Preferences

GrafNet Display

See *Section 2.6.8, Preferences* on page 61 for information regarding any options not described here.

Zoom Display Settings

The *Ellipse scale* field changes the size of the error ellipses. Projects covering large areas might have large ellipses and decreasing the values for all three zoom scales (0, 1, and 2) will make the ellipses smaller.

Error Ellipse Display

Controls whether relative or absolute error ellipses are displayed. First, error ellipses can be displayed for session solutions. Second, ellipses can be displayed for the stations after a network adjustment is run. The crosses on the ellipse option shows the axes of the error ellipses.

Solution

In addition to the options described in *Section 2.6.8, Preferences* on page 61, the *Solution* tab offers GrafNet users the ability to automatically run a network adjustment after processing has completed.

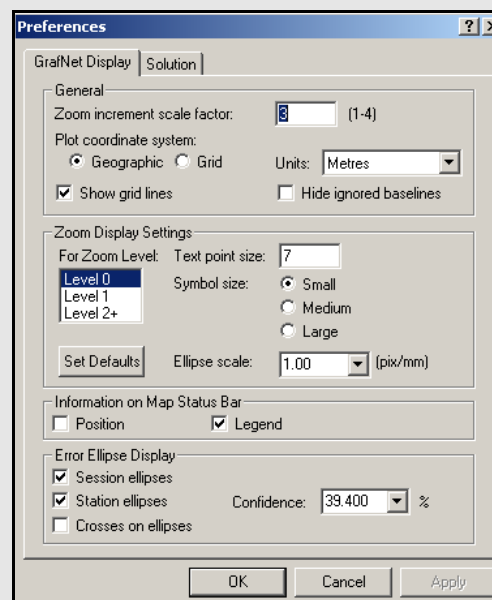
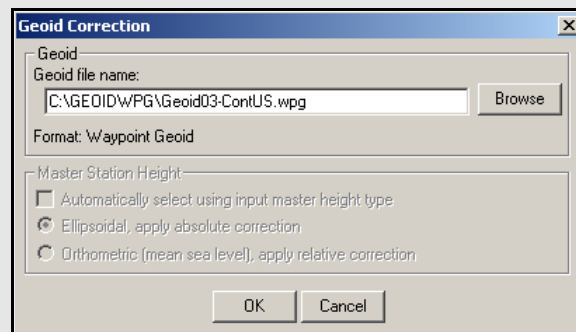
3.6 Output Menu

3.6.1 Export Wizard

See *Section 2.7.5, Export Wizard* on page 72 for information regarding this feature.

3.6.2 View Coordinates

Opens the last file generated by the Export Wizard in the internal ASCII viewer.



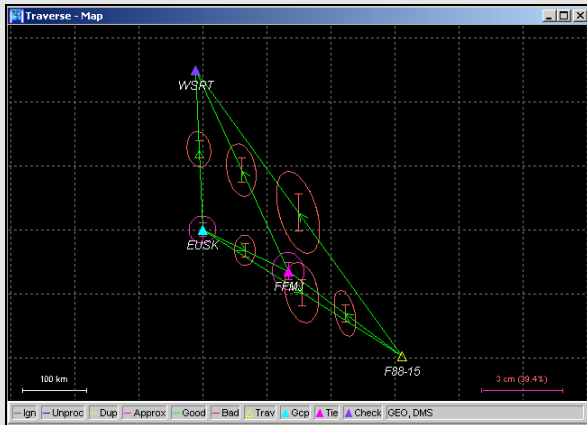


Table 13: Station Colour Legend

Color	Description
Cyan	Control point – A reference station with known coordinates
Dark Purple	Check point – Station has known coordinates available, but they will only be used as a check. Comparisons are found in the TRV file. The network adjustment output file (NET) also shows check point residuals.
Light Purple	Tie point – Two or more sessions are connected as remotes to this station via the traverse solution. The TRV file will show traverse ties.
Yellow	Traverse point – No tie information can be computed for the traverse solution.

3.6.3 Export DXF

See *Section 2.7.9, Export Binary Values* on page 77 for information regarding any feature not described below. Only the options specific to GrafNet are discussed here.

Station Error Ellipses

Display around each station and is only available if a network adjustment has been completed.

Baseline Error Ellipses

Only the baselines that need to be processed.

Error ellipse scale factor

The ellipse scale factor scales the ellipses so they will be visible if you do not see them in the DXF file.

3.6.4 Show Map Window

Map Window

This window displays a graphical representation of the project area. It shows the stations and connecting baselines.

Mouse Usage in Map Window

Either double-clicking or right-clicking on a station, gives you access to several options, which are described in *Section 3.6.5, Show Data Window* on page 124.

-
- ☒ Clicking on a station displays the station in the Stations window of the Data Manager, while clicking on a baseline will display that baseline and any duplicates in the Sessions window.
-

3.6.5 Show Data Window

Data Manager

This interactive window allows for easy display and organization of the project components. The *Data Manager* gives statistical information regarding all observations and baselines, among other things.

Observations Window

The *Observations* window displays information regarding all the observation files (GPB) that are included in the project. The columns that are in the shaded box are displayed in the *Observations* window. The following options are available by right-clicking on an observation:

View

Displays the *Information* window for the observation file.

Edit

Opens the *Add / Edit Observation* window, in which the station name and antenna information can be corrected.

Delete Observation

Removes the observation period from the project.

View GPB File

Opens the observation file in *GPB Viewer*.

View STA File

Opens the station file for the associated GPB file.

View Ephemeris File

Opens the ephemeris file (EPP) for the associate GPB file.

Plot Coverage

Opens the *File Data Coverage* plot for all observations in the project. See *Table 1, Common Plots* on page 67 for information regarding this plot.

Plot L1 Satellite Lock

Launches the *L1 Satellite Lock / Elevation* plot. See *Table 1, Common Plots* on page 67.

Plot L2 Satellite Lock

Launches the *L2 Satellite Lock / Elevation* plot.

Show Sessions using Observation

Displays all sessions involving the observation period in the *Sessions* window.

Expanding the Observations branch in the Data Objects window on the left-hand side of the Data Manager allows the observations to be displayed individually in the Observations window. Expanding each observation in the Data Objects window displays the station that was observed.

Columns in the Observation Window

Name

Name of the station at which the observations were made.

AntHgt

Antenna height for the period at which the observations were made.

AntType

Type of antenna used at the station.

File

File, path and name of the GPB observation file.

#

If multiple observations periods are contained within one GPB file, this column indicates which of those observation periods is being referred to. Observation periods are numbered sequentially in the order they appear in the GPB file.

Length

Length of the observation period.

Start Date

Date when the observation period started.

Start Time

Time of day at which the observation period started.

Receiver

Type of receiver used to log observations.

Freq

Indicates whether data is single or dual frequency.

Int(s)

Interval, in seconds, at which the data was logged.

Columns in the Stations window

Name

Name of station.

Type

See *Table 13, Station Colour Legend* on page 124 for information on station types.

Latitude

Latitude coordinate of the station.

Longitude

Longitude coordinate of the station.

EllHgt

Ellipsoidal height of the station.

Source

Indicates whether the station coordinates are from the traverse solution or the network adjustment.

#Files

Number of observations periods for that station.

TotalLen

Total observation time made at that station.

A(mm)

Semi-major axis of error ellipse at that station, as defined from the network adjustment.

B(mm)

Semi-minor axis of error ellipse at that station, as defined from the network adjustment.

DH(mm)

Estimated height standard deviation.

Stations Window

The *Stations* window displays information regarding all the points observed in the network. The columns listed in the shaded box are displayed in the *Stations* window. The following options are available by right-clicking on a station:

View Solution

Displays the solution from traverse computation and network adjustment, if valid.

Add as Control Point

Allows you to define the station as a control point.

Add as Check Point

Allows you to define the station as a check point.

Edit Control / Check Point

Allows for editing of the input coordinates of stations already defined as check or control points.

Toggle between Control / Check Point

Switches status between control point and check point.

Add to Favourites

Adds the station to the *Favourites* list, using the computed coordinates.

Remove Processing Files

Removes all observation files logged at that station from the project.

Show Observations

Displays all observation periods for that station in the *Observations* window.

Show Connecting Sessions

Displays all sessions involving that station in the *Sessions* window.

Expanding the *Stations* branch in the *Data Objects* window on the left-hand side of the *Data Manager* allows for the stations to be displayed individually in the *Stations* window. Further expanding each station in the *Data Objects* window displays all observation files in which the station was observed.

Sessions Window

The *Sessions* window displays information regarding all the sessions in the network. The columns listed in the shaded box are displayed in this window. The following options are available by right-clicking on a session:

View Results

Displays the results of forward or reverse processing, or the combined solution.

View Information

Displays the *Information* box for the session.

View File

Opens the message log, static summary, trajectory output or configuration files.

Plot

Launches the plots discussed in *Table 1, Common Plots* on page 67.

Options

Allows access to the processing settings so that they can be set individually for this session. See *Section 3.4, Process Menu* on page 112 for additional information.

Override Status

Manually sets the status of the session. See *Table 11, Solution Types* on page 102 for information. Ignore redundant or troublesome sessions. You can assign a *Good* status to a failed baseline if the solution is, in fact, correct. Only do this on closed loop networks.

Process

Processes the session independently of all others.

GrafNav

Launches the baseline into GrafNav. See *Section 2.5, Process Menu* on page 42 for additional information.

Delete

Deletes all of the processing files related to that session, or deletes either the forward or reverse solution.

Compute Azimuth / Distance

Displays the *Distance and Azimuth* box for the session. See *Section 2.8.2, Distance & Azimuth Tool* on page 83 for help.

Show To / From Stations

Displays both stations in the *Stations* window. See *Stations Window* on page 126 for information.

Show To / From Observations

Displays both station *Observations* windows. See *Observations Window* on page 125 for information.

Expand the *Sessions* branch in *Data Objects* of the *Data Manager* to display individual sessions in the *Sessions* window.

Columns in the Sessions Window

Name

Name of the session, which serves to indicate direction of coordinate transfer.

SD

Standard deviation, in mm, of the baseline as calculated by the Kalman filter.

Reliability

Reliability of the fixed static solution, if available.

RMS

RMS of the fixed static solution. Applies only to fixed baselines.

SolType

Indicates solution type. See *Table 11, Solution Types* on page 102 for a full description.

Time

Length of session, in *hh:mm* format.

Dist

Baseline distance, in km.

Status

Solution status. See *Table 11, Solution Types* on page 102 for descriptions.

From

Indicates the *FromStation*.

To

Indicates the *ToStation*.

#

If multiple sessions exist for the same baseline, indicates which session is being referred to.

Columns in the Control / Check Points Window

Name

Name of the station.

Type

Type of control or check point, which can be 3D, horizontal or vertical.

Latitude

Known latitude coordinate of the station.

Longitude

Known longitude coordinate of the station.

EllHgt

Known ellipsoidal height of the station.

HzSD

Standard deviation of the known horizontal coordinates.
Applies only to control points.

VtSD

Standard deviation of the known vertical coordinate.
Applies only to control points.

dE

Easting residual between input coordinate and traverse solution at check point.

dN

Northing residual between input coordinate and traverse solution at check point

dH

Height residual between input coordinate and traverse solution at check point

Control / Check Points

The *Control / Check Points* window displays information regarding all the stations assigned known coordinates in the network. The columns listed in the shaded box are displayed in the *Control / Check Points* window.

The following options are available by right-clicking on a control or check point:

View Info

Displays the *Information* box for the point.

Edit

Allows for editing of known coordinates via the *Add / Edit Control Point* window.

Toggle between Control / Check

Switches status between control point and check point.

Show Station

Displays the station in the *Stations* window. See *Stations Window* on page 126 for information.

Expanding the Control or Check Points branches in the Data Objects window on the left-hand side of the Data Manager allows for the points to be displayed individually in the Control / Check Points window.

3.6.6 Baselines Window

The *Baselines Window* displays information regarding all the sessions in the network. See *Columns in the Sessions Window* on page 127 for a description of the columns displayed and the options available by right-clicking on a session.

Expanding the *Baselines* branch in the *Data Objects* window on the left-hand side of the *Data Manager* allows for the sessions to be displayed individually according to the baseline they are expanded from. Expanding each baseline in the *Data Objects* window allows for the display of any individual session in the *Sessions* window.

3.6.7 Processing Window

See *Processing Method* on page 42 for information regarding this window.

3.7 Tools Menu

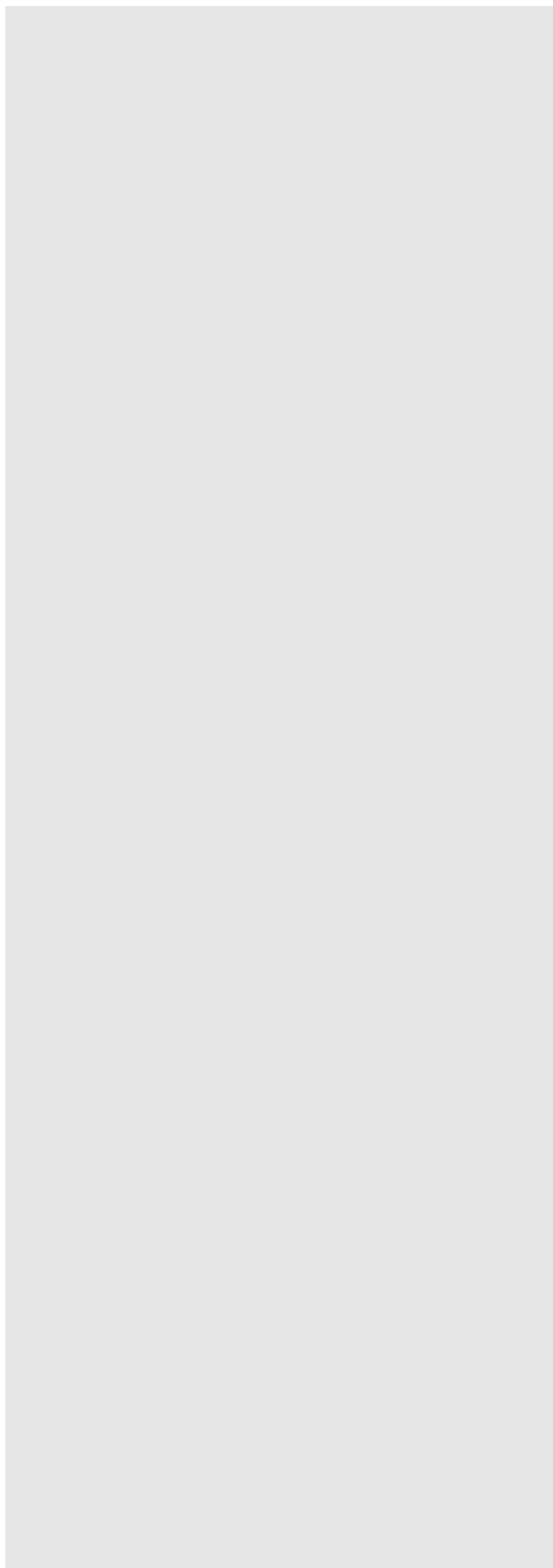
See *Section 2.8, Tools Menu* on page 83 for information regarding the features available through this menu.

3.8 Help Menu

See *Section 2.10, Help Menu* on page 100 for information about these features.

Table 14: Baseline Color Legend

Color	Description
Blue	Unprocessed – Normally represents an unprocessed baseline. In some cases when processing quits prematurely, the color may remain blue. The return error message can be viewed by right-clicking the baseline in the <i>Sessions</i> window of the <i>Data Manager</i> and selecting <i>View Information</i> .
Grey	Ignored – Indicates a session that is to be ignored.
Yellow	Duplicate – Indicates a duplicate baseline, meaning that it has more than one session. Such baselines are plotted with two colors, with one being yellow. The second color represents the best solution among all the sessions for the duplicate baseline.
Purple	Approximate – Indicates that an error has occurred during the processing and only an approximate (1 to 5 metres) solution was extracted. Such a solution is only useful for transferring an approximate position from base to remote. This session should either be reprocessed or ignored.
Red	Bad / Failed – Represents a baseline where processing failed one or more tests and is thus deemed to be bad. Right-click the baseline in the <i>Sessions</i> window of the <i>Data Manager</i> and select <i>View Information</i> to determine the problem. If you are confident that the solution is okay, the status can be changed from the <i>Sessions</i> window as well. You can control when float solutions pass via the <i>Solution</i> tab under <i>Options Preferences</i> .
Green	Success – Indicates a session that has passed all tests.



4.1 Overview of the File Formats

4.2 CFG File

A CFG file is a GrafNav project file. This file is written by GrafNav when creating a new project, and contains all processing options used in the project. The name of the CFG file defines the name of all ASCII and binary files written by GrafNav when processing.

4.3 GPS Data Files

The following files are produced by GrafNav's raw GNSS data conversion utility.

4.3.1 GPB File

Raw code, carrier and Doppler measurements are converted to a GPB file. These are the raw measurements required for post-processing. Also written to the GPB file is a position for each measurement epoch, date and time information and other information.

GPB files can be opened within GrafNav's *GPB Viewer*, which allows you to view the raw measurements collected and perform basic editing functions if needed. GPB files can also be converted to RINEX using the GPB to RINEX utility.

4.3.2 STA File

A station file contains any decoded camera marks, antenna heights and station names. It is read automatically by GrafNav when adding a GPB file to a project. The first line of a station file should contain \$STAINFO.

The station file may have a header record. The header is optional and will not be present in most cases. The following is a description of the header format.

```
Hdr {
  Proj:      "Name of Project"      Field project name
  User:      "User Name"           Name of field operator
  Time:      hh:mm:ss LOCAL/GMT     Start time
  Date:      mm/dd/yyyy            Start date
  RxName:    Receiver              Receiver type
  RxSub:     Model                 Receiver sub type
  Hi:        Hi_m VERT/SLANT        Antenna height, measured vertically or slanted
  Ant:       V_Offset H_Offset "Name" Antenna info (vertical offset to phase center, horizontal distance to measurement mark, antenna model name)

  Pos:       phi lamda ht ELL/ORTHO Computed position of antenna
  Mode:      SP/DGPS/RTFL/RTFX/RTK/FIX Mode of solution (RTFL=float, RTFX=fixed, RTK=float/fixed not known, SP=single point, GPS=DGPS, FIX=known)
}
```

The following is the format for the stationary station marks:

```
Sta {
  *ID:       "Station ID"
  *GTim:     SecOfWeek [WeekNo]     GPS Time
  UTim:      SecOfWeek [WeekNo]     UTC Time could be used instead of GTim but this is not recommended and often not supported.

  Pos:       phi lamda ht ELL/ORTHO Computed position of antenna
  Mode:      SP/DGPS/RTFL/RTFX/RTK/FIX Mode of solution (RTFL=float, RTFX=fixed, RTK=float/fixed not known, SP=single point, DGPS=DGPS, FIX=known)

  Std:       SdE SdN SdH           Standard deviation, in metres
  Hi:        Hi_m VERT/SLANT        Antenna height, measured vertically or slanted
  Ant:       V_Offset H_Offset "Name" Antenna info (vertical offset to phase center, horizontal distance to measurement mark, antenna model name)

  OffR:      Range TrueAzimuth DH  Offset to actual point (2D range in metres, azimuth in degrees, height difference in metres)

  OffL:      DE DN DH              Offset in local level frame, in metres
  OffB:      DX DY DZ              Body frame offset, where X-RightWingPos, Y-ForwardPos, Z-UpPos

  Att:       roll pitch heading    Attitude, in degrees
  Desc:      "description"
  Rem:       "remarks"
  Nsv:       NumSats NumGPS NumGlonass
  Dop:       PDOP HDOP VDOP
  Rms:       L1Phase CACode
  Age:       Sec                  Age of last correction or RTK receipt
  Enable:    1/0                  Used in GrafNav
}
```

☒ * indicates a required field.

The station file format also handles event marks. Saving a project with event marks loaded brings the event marks into the station file. The following is the event mark format.

```
Mrk {
  *Event:  Number          Event number or name (no spaces)
  Desc:    "Name"          Roll name
  *GTim:   SecOfWeek [WeekNo] GPS Time
  *UTim:   SecOfWeek [WeekNo] UTC Time could be used instead of GTim but this is not
                                recommended and often not supported
  Pos:     phi lamda ht ELL/ORTHO Computed position
  Mode:    SP/DGPS/RTFL/RTFX/RTK/FIX Mode of solution (RTFL=float, RTFX=fixed,
                                RTK=float/fixed not known, SP=single point, DGPS=DGPS,
                                FIX=known)
  Std:     SdE SdN SdH      Standard deviation, in metres
  Vel:     VE VN VH         Velocity, in m/s
  Att:     roll pitch heading Attitude, in degrees
  Rem:     "remarks"
  Nsv:     NumSats NumGPS NumGlonass
  Dop:     PDOP HDOP VDOP
  Rms:     L1Phase CACode
  Age:     Sec              Age of last correction or RTK receipt
  Enable:  1/0              Used in GrafNav
}
```

☒ * indicates a required field.

Another data type handled in the station format is an RTK epoch, where every epoch can be recorded.

```
RTK {
  *GTim:   SecOfWeek [WeekNo] GPS Time
  *UTim:   SecOfWeek [WeekNo] UTC Time
  *Pos:    phi lamda ht [ELL/ORTHO] Computed position
  Mode:    SP/DGPS/RTFL/RTFX/RTK/FIX Mode of solution (RTFL=float, RTFX=fixed,
                                RTK=float/fixed not known, SP=single point, DGPS=DGPS,
                                FIX=known)
  Std:     SdE SdN SdH      Standard deviation in metres
  Vel:     VE VN VH         Velocity, in m/s
  Att:     roll pitch heading Attitude in degrees
  Nsv:     NumSats NumGPS NumGlonass
  Dop:     PDOP HDOP VDOP
  Rms:     L1Phase CACode
  Age:     Sec              Age of last correction or RTK receipt
  Enable:  1/0              Used in GrafNav
}
```

☒ * indicates a required field.

4.3.3 EPP File

Waypoint's software uses a custom ASCII file format for the ephemeris records. These records are created by the *Convert Raw GNSS data to GPB* utility. Duplicate records will be automatically ignored by the software.

4.4 Output Files

This section discusses some of the output files created when processing with Waypoint software.

4.4.1 FML & RML Files

The *Forward Message Log* and *Reverse Message Log* files contain all of the messages generated by the processing engine. Some common messages are described here:

Reading ephemeris files...

Processing ephemeris file 'C:\GPSData\rover_.epp'

Detected 40 GpsEph, 0 GlonassEph, 0 GpsIono and 0 GpsAlmanac records

This message is generated just prior to processing. GrafNav combines all ephemeris measurements at the base and rover before processing.

Best base on BL1 is PRN 17 with 4 points and elevation of 62.1 degrees

Second best on BL1 is PRN 16 with 2 points and elevation of 51.7 degrees

This message indicates the base satellite (and its elevation) selected after a base change or at outset. The second best base is also shown. Base satellite selection is based on a point system that includes a number of factors such as elevation above the horizon and whether it is rising or falling.

Detected bad Phase measurement @ 9.1 sigma. Rms is 0.336 m (Worst Prn is 14 on B/L BL1 with residual of 0.465)

This can be caused by undetected cycle slips or noisy measurements due to a challenging GNSS signal environment. GrafNav's outlier detection routines will attempt to fix the problem by rejecting individual measurements and recomputing the residual.

+++ ARTK obtained a valid integer fix on BL BL1

Fixed 8 out of 8 satellites at a distance of 8.3 km

Residual RMS is 2.47 mm, Reliability is 3.8, Float-fix-sep. is 0.243 m

ARTK not engaged--rewind ignored

ARTK success!

Message displayed for a successful ARTK fix

Epoch rejected due to poor satellite geometry--DD_DOP of 918.0 too large

This message warns that an epoch has been rejected because of poor satellite geometry.

Doppler L1 cycle slip on PRN 24 of 1575419.57 cycles on baseline BL1

Indicates that a large change in carrier phase has been detected which is interpolated as a cycle slip.

Locktime cycle slip on PRN 4 of -5.92 cycles on baseline BL1

Cycle slip has been reported by base or remote receiver.

Inserted L1 cycle slip due to locktime reset for PRN 4 on baseline BL1

Receiver cycle slip counter reset at some time in the past but was not caught. Therefore, slip inserted now.

Less than four satellites at startup--Will try next epoch(s)

Software needs at least 4 satellites and good measurement quality at startup.

Warning: Epoch with less than 4 good satellites (Cycle slips)

This message warns about an epoch with less than 4 satellites.

Locktime cycle slip on PRN 26 of -41.31 cycles on baseline BL1

Small L2 cycle slip on PRN 26 of 0.65 cycles on baseline BL1

Both messages warn of cycle slips on L2. The DPH is an indicator of the size of the cycle slip. It shows the difference in phase. If the data contains many L2 cycle slips, it will make for a bad ionospheric-free solution. If there are many L2 cycle slips, try using the relative ionospheric solution.

Prn 15 is below mask angle of 10.0 degrees

This message indicates that a satellite has gone below the elevation mask.

Satellite 7 is rising or re-appearing

This message is usually caused from a satellite on the horizon.

Prn 27 disappeared for 33.0 seconds on baseline BL1

Indicates that as the satellite dropped out and is reappearing, a new ambiguity will be solved.

Calculating fixed solution**Calculating RMS values**

Continuous fixed solution reliability: 7.43 (PASSED), RMS: 0.0372 m (PASSED), STD: 0.0014 m

Continuous fixed solution position is: 39 01 23.54716, -84 36 21.25817, 259.7909 m

Computing New Fixed solution

This message shows the results from the multi satellite fixed solution. The reliability is the ratio between the second best RMS and the best RMS. The minimum reliability for a pass is 1.35. The RMS is the RMS fit of the fixed solution. This number is in metres and the maximum value to pass is 0.025 m + 1PPM for dual frequency and 0.015 + 1PPM for single frequency.

Warning: No precise ephemeris available for prn 21

Message warns that a precise ephemeris is missing for a satellite. The user may want to try another SP3 file to better the results.

\$\$\$ GPS data errors detected--will try and reject measurements, baselines or satellites

Error messages starting with \$\$\$ indicate bad carrier or code measurements encountered. The above message should be following another message indicating what residuals are out-of-range and which satellite has the largest value. The indicated satellite may not be the actual problem one because the Kalman filter distributes the errors around. A number of tests will be performed to isolate the problem data and satellite. Therefore, this message is followed by the messages shown below.

On code, worst PRN is 20, RMS is 1.46 m (PASS), reliability is 1.84 (FAIL)

A further test on the combined code-carrier solution to ensure that the code is OK.

On phase, worst PRN is 28, RMS is 0.0949 m (PASS), reliability is 1.19 (FAIL)

This test will generally indicate if a missed cycle slip to other carrier phase problem was fixed by removing a particular satellite. The above message indicates that the problem could not be fixed, and will generally be followed by a filter reset message. See below. The reliability must be greater than 4.0 to be signaled as a pass. The user should investigate the clock offset information at this epoch via *GPBView* to see if the problematic epoch is due to an incorrectly computed clock shift.

\$\$\$ Engaging filter reset--Accuracy is severely reduced

This is printed when the filter reset is being engaged. It should be preceded by a message indicating why the filter reset was issued. A filter reset is when a cycle slip is issued to all satellites and the position is reset to startup values.

(+) ARTK engaged due to occurrence of filter reset

Following any filter reset, ARTK is re-engaged

Locktime and doppler cycle slip on PRN 30 of -307.64 cycles on baseline BL1

Indicates that a cycle slip has occurred and it has been detected by both the locktime and a large change in the carrier phase.

%%% PRN 18 was omitted for time range 488400.0-488500.0 s on ALL baselines

%%% ALL satellites were omitted for time range 8000.0-8100.0 s on baseline mast

'%%%' followed by a message indicates when and how long a baseline and/or PRN was omitted from processing.

4.4.2 FSS & RSS Files

Reported in the solution summary files is a summary of each ARTK fix and static session.

Configuration and processing settings

Project settings:

```

Master 1      : Name      GRN04-0107a    ENABLED
               : Antenna   SIMPLE_VERT   0.000 m
               : File      \\waypoint01\c\GPSData\Manual_Data\GRN04.gpb
               : Position  43 45 49.97515 -87 50 51.75271 198.262
Remote        : Name      Remote          ENABLED
               : Antenna   SIMPLE_VERT   0.000 m
               : File      \\waypoint01\c\GPSData\Manual_Data\air_rover.gpb
               : 0 static sessions
Direction     : FORWARD
Process Mode   : Dual frequency carrier phase
Static Initial. : Float
Use AR         : Yes
Use Glonass    : Yes

```

The file may look different depending on whether static or kinematic processing was performed. When static processing, the output includes the final coordinates and various statistics associated with those coordinates. In kinematic processing, the ARTK summary record is the only output if ARTK resolved carrier phase ambiguities.

The following is the output satellite tracking list. This output is only displayed on fixed static solutions. It shows which satellites are tracked when, how long, and the status of the satellite. The status is important because it will show if any satellites are rejected. This output can also be seen for all data types in the plot *Satellite Lock*.

Session: 511, Base: BL1, Satellite status in fixed solution

PRN	START	END	DT (SEC)	BASE	BEST RMS	INDEX	RMS@0	NUM RMS	NEPOCH	STATUS
21	149910	151050	1140.0	2	0.044	0	0.044	39	39	Rejected
10	142530	151260	8730.0	2	0.022	0	0.022	292	292	OK
26	148740	151260	2520.0	2	0.028	0	0.028	85	85	OK
29	146820	151260	4440.0	2	0.033	0	0.033	149	149	OK
21	151740	151950	210.0	6	0.038	0	0.038	8	8	Rejected
18	151710	152130	420.0	6	0.024	0	0.024	15	15	OK
10	151350	154770	3420.0	6	0.013	0	0.013	115	115	OK
10	155070	155280	210.0	6	0.018	0	0.018	8	8	OK

Following are the final coordinates that are output in a static solution. The difference between the fixed and float output is the fixed will have an RMS and reliability. The RMS represents the fit of the carrier phase measurements in the solution. The reliability is the ratio between the second best RMS and the best RMS.

Final FIXED static position for Station STATIC, Base BL1

```
Static {
    ToSta:          "STATIC"
    FromSta:        "BL1"
    IsBest:         Yes
    AntHgt:         0.486 m

    StartTime:      6240.00 1318 01:44:00.0 04/10/2005
    EndTime:        6375.00 1318 01:46:15.0 04/10/2005
    TimeLen:        2 minutes, 15 seconds

    Latitude:       -39 00 33.18453
    Longitude:      174 10 46.74393
    EllHeight:      63.8096
    SolType:        L1L2-Fixed
    IsFixed:        Yes
    RMS:            0.0040 PASS ; m
    Reliability:    10.3 PASS ; RMS ratio

    StdDev:         0.0063 0.0068 0.0147 ; m (e,n,h)
    EcefVec:        45.4059 -48.5693 -63.9423 ; m
    EcefCov1:       2.02423923e-004
    EcefCov2:       -5.94309046e-005 4.99990537e-005
    EcefCov3:       6.87795183e-005 -1.87233603e-005 5.03819486e-005
    AvgDDDop:       3.35
    AvgPDop:        2.12
    AvgNumSats:     7.0
    Quality         1

    SlopeDist:      92.246 ; m
    HorizDist:      92.235 ; m
    SurfaceDist:    92.235 ; m
    Azimuth12:      151 42 36.21749
    Azimuth21:      331 42 35.07388
}
```

The only output from kinematic processing is the ARTK summary record as shown below. Note that if kinematic processing is used without ARTK, no output will be shown in the FSS/RSS files.

KAR summary records for succeeded solutions

```
Kar {
  EngageTime:  343269.00 1272 23:21:09.0 05/26/2004
  RestoreTime: 343270.00 1272 23:21:10.0 05/26/2004
  SearchTime:  343329.00 1272 23:22:09.0 05/26/2004
  TimeSkipped: 0.0      s
  TimeUsed:    60.0     s      PASS
  RMS:         0.010    cyc     PASS
  Reliability: 6.2              PASS
  FloatFixSep: .42       m      PASS
  SearchDist:  0.02     km      "HIGH L2 noise model"
  AvgDist:     0.02     km
  AvgSats:     7.0
  SearchSats:  7        "13 3 19 1 28 27 31"
  RestoreSats: 7        "13 3 19 1 28 27 31"
  RestoreDop:  2.6
  RestorePos:  -21 10 09.12638 149 11 00.32129 58.989
  Message:     "KAR success!"
}
```

4.4.3 FWD, REV, CMB, FSP, RSP and CSP files

FWD, REV and CMB files are created in differential processing whereas FSP, RSP and CSP files are created in PPP. A trajectory record is written for each processed measurement epoch. The combined processing results (CMB or CSP) is usually what the Export Wizard accesses in order to customize formatted results.

\$OUTREC Ver8.50.1220 NGPS32 Forward Extended

; Processed by Unknown, description: Run (29)

; Time and date is: 21:36:29, 01/23/2013

; Waypoint Products Group, Copyright NovAtel Inc., 1992-2012

```
;Out { Tim: even_sec_time corrected_time WkNum          ; GPS seconds of the week, week number
;      Geo: latitude longitude height anthgt           ; Degrees minutes seconds, metres
;      Loc: d-east d-north d-height v-east v-north v-height ; local level pos+vel, metres, m/s
;      Sta: quality amb_drift dd_dop pdop hdop vdop      ; 1-6, cycles/sec, dops
;      Rms: L1Rms CARms P2Rms D1Rms L1Std CASTd D1Std   ; m, m/s Rms=RMS of residual, Std=measured std-dev
;
;      Var: cee cnn czz cve cvn cvz cpos              ; Position + velocity variance + trace with ppm, m2, m2/s2
;      Flg: S/K L/F NumGps NumGlonass SolType          ; (S)tatic, (K)inematic, f(L)eat amb., (F)ixed amb.
;                                                       ; SolType: (S)-SF carrier, (D)-DF carrier,
;                                                       ; (I)-IonoFree, (R)-RelIono, (C)-C/A Only
;      Cov: cne cze czn cvne cvze cvzn                ; Position and velocity covariance
;      Ecf: dx dy dz                                   ; ECEF base->remote vector
;      Acc: ae an au                                   ; Local level accelerations (m/s2)
;      Bli: nBl Flg1(U,N,R) nS1 Wgt1 Dst1 Flg2 nS2 Wgt1 Dst1 Wgt2 Dst2 ...
;                                                       ; nBl=#baseline, Flg: U=used, N-not-valid, R-Rejected,
;                                                       ; nSats=# satellites used, Wgt=weight (0-1)
;                                                       ; Dst=distance in km
;      Bls: iBl nSats Prn1 B/R/Amb1 Prn2 B/R/Amb2 Prn3 B/R/Amb3 ...
;      Bls: ...                                       ; iBl=0,1,...,nSats=# sats, B=BASE,R=REJECTED,
;                                                       ; Amb=DD Ambiguity
;}
```

A numerical example is also given:

```
Out { Tim: 321665.000 321665.000000053 1690
      Geo: 39 59 13.03501 -83 04 07.44637 196.8868 2.110
      Loc: -1962.100 3020.551 11.551 0.016 -0.012 -0.088
      Sta: 6 1.000000 6.67 3.26 1.65 2.82
      Rms: 0.0000 1.690 0.000 0.008 0.0195 2.931 0.977
      Var: 3.69047e+000 2.39072e+000 2.50583e+001 4.10052e-001 2.65636e-001 2.78426e+000 3.11395e+001
      Flg: K L 6 0 D
      Cov: -5.22128e-001 -6.04875e+000 3.19914e+000 -5.80144e-002 -6.72084e-001 3.55460e-001
      Ecf: -2181.475 1679.322 2322.658
      Acc: 0.000 0.000 0.000
      Bli: 1 U 6 1.00 3.6
      Bls: 0 6 30 B 32 -5549212.283 20 -7678228.525 16 -26349873.378 23 -35794199.949 31 -3923372.058
}
```

4.4.4 FBV & RBV Files

Binary Value files contain individual satellite residuals and multi-base data which is not written to the standard output files. These files contain:

For each baseline:

- i. Code, carrier and Doppler RMS values
- ii. Code, carrier and Doppler SD values
- iii. Code and carrier phase separation values
- iv. DOP values
- v. Ambiguity drift
- vi. Effective weighting

For each satellite:

- i. PRN
- ii. Baseline
- iii. Rejection + base satellite flags
- iv. Code, carrier and Doppler residual values
- v. Code, carrier and Doppler SD values

Export these files to ASCII in GrafNav via the *Export Binary Values* feature. See *Section 2.7.5, Export Wizard* on page 72 for additional information.

5.1 Utilities Overview

This chapter describes the following utilities that are included with Waypoint's software:

- GPB Viewer
- Concatenate, Slice and Resample
- GNSS Data Converter

This chapter goes through each menu of their interfaces. Step-by-step instructions for first time users are also included.

5.2 GPB Viewer Overview

GPB files are in a binary format and cannot be viewed with a normal text editor. *GPBViewer* allows you to both view and edit your raw GNSS data.

5.2.1 File

5.2.1.1 Open

Any GPB file can be opened with this feature.

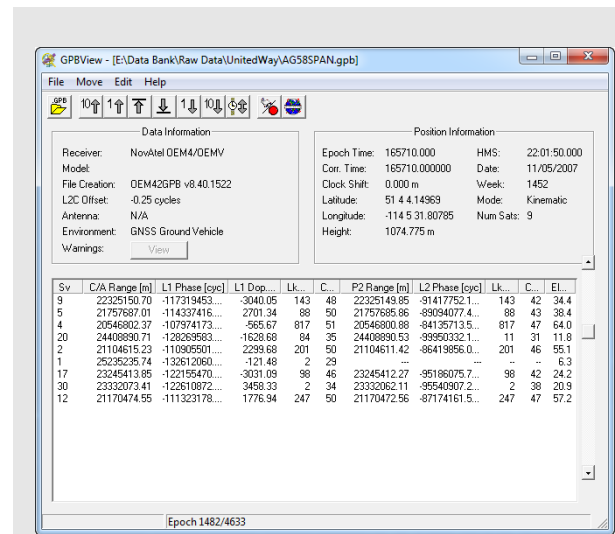
-
- ☒ If the GPB file is corrupt, *GPBViewer* prompts for permission to fix the file.
-

5.2.1.2 Close

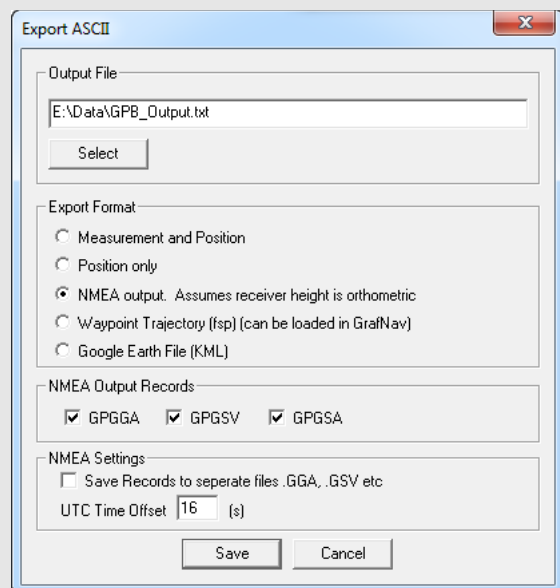
This feature closes the GPB file without exiting from *GPBViewer*.

5.2.1.3 Save As

If you are making modifications to a GPB file (such as the static/kinematic flag), this feature can be used to create a copy of your file prior to making any changes. An associated ephemeris file (.epp) will automatically be written when using the *Save As* feature.



-
- ☒ L2C tracking is indicated as a C2 after the satellite.
-



ASCII formats for saving files

Measurement and Position

Exports time, date, raw measurement data and position information for each epoch.

Position only

Exports time, date and position information for each epoch.

NMEA output

GPGBA, GPGBV and GPGBA strings can be exported using this option.

Waypoint Trajectory

Exports the data in Waypoint's single point trajectory (FSP) format. This trajectory file can then be loaded into GrafNav as a solution. See *Chapter 4, File Formats* on page 131 for a definition of the format.

Google Earth

Exports position information into a KML file, which can then be opened within Google Earth.

5.2.1.4 Export ASCII

This feature saves data from the binary GPB file into various ASCII formats.

Output File

This option allows you to name the output file. Provide a filename extension because the software will not automatically assign one.

Export Format

The export formats available when saving a GPB file to ASCII are explained in the shaded box.

5.2.1.5 Load Alternate Ephemeris File

The GPB viewer uses ephemeris data to calculate and display satellite elevations at each epoch. If no ephemeris data was decoded, an alternate ephemeris file can be loaded here. Ephemeris data is required when performing certain editing functions within the GPB viewer.

GrafNav's *Download Service Data* utility can be used to download and convert GNSS broadcast ephemeris data. See *Section 2.8.12, Download Service Data* on page 94 for more information.

5.2.1.6 Exit

Exits the program.

5.2.2 Move

Forward *n* and Backward *n*

Scrolls through *n* epochs in the direction indicated.

Start of file and End of file

Moves to the first and last epoch in the file.

-
- ☒ It is easier to scroll through the GPB file using the shortcut keys, specified under the *Move* menu beside each option.
-

Search

Moves to a specific location in the file. You can specify an epoch number or a time, in either GPS seconds of the week or GMT format.

5.2.3 Edit

Several options under this menu make permanent changes to the GPB file. Prior to doing so, you may wish to create a copy of the original file using the *Save As* option under the *File* menu.

5.2.3.1 Switch Static/Kinematic...

GrafNav's processing mode (static or kinematic) is determined by the static/kinematic flag decoded to the GPB file. This flag is normally set during decoding, however it can be altered after decoding using this option.

-
- ☒ The static/kinematic flag is found in the *Position Information* section of the GPB Viewer.
-

Process Mode

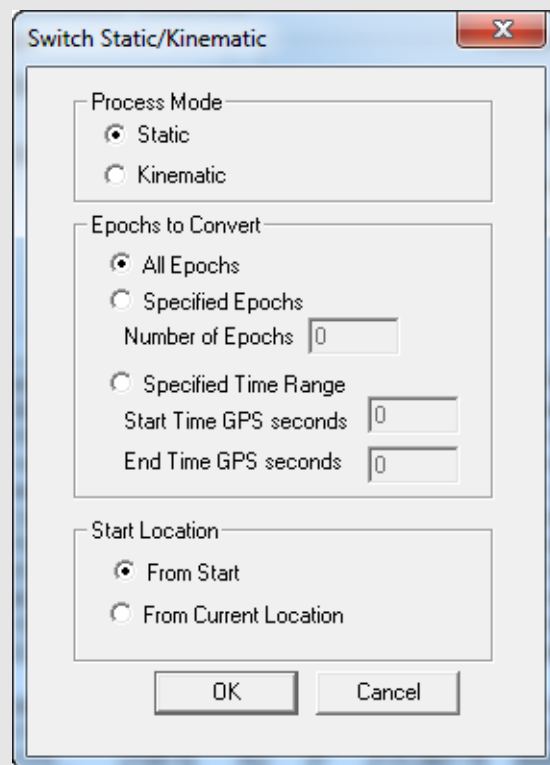
Specifies whether the mode is to be set to *Static* or *Kinematic*.

Epochs to Convert

Determines which epochs will be switched. See the shaded box for more information.

Start Location

Use in conjunction with *All epochs* and *Specified Epochs*, under *Epochs to Convert*. Determines the starting point of the conversion.



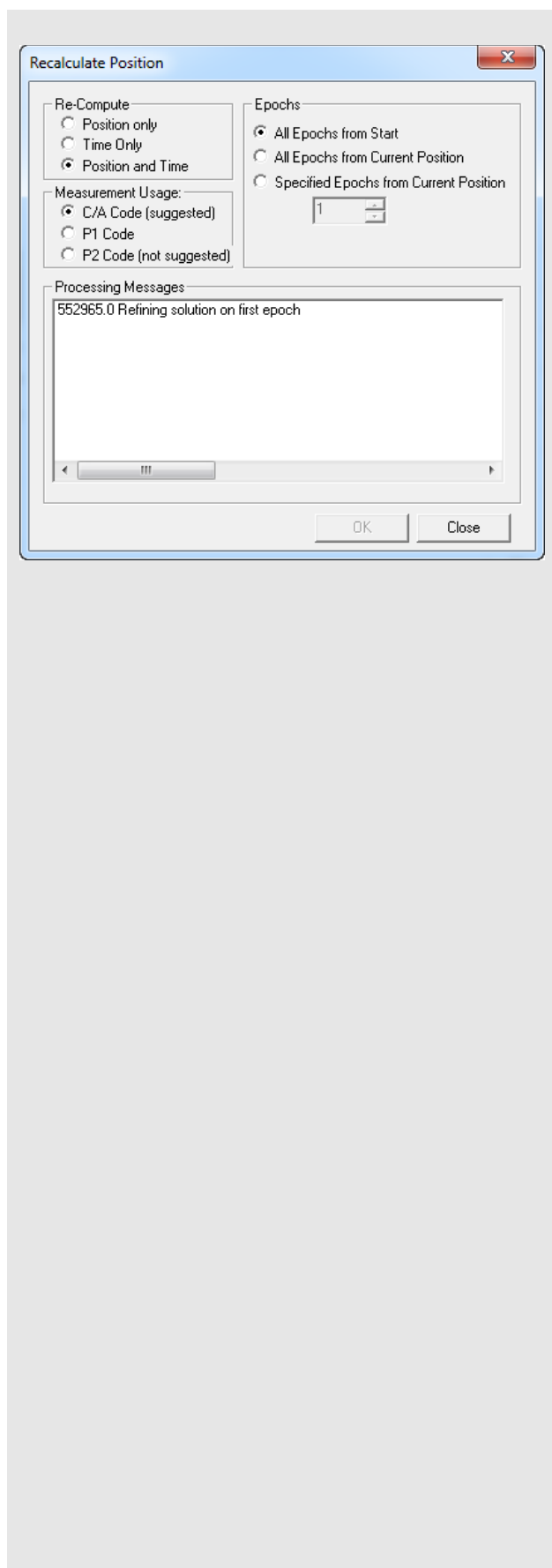
Epochs to Convert options

All Epochs

Switches all epochs from the start of the file onwards or from the current location onwards, depending which starting point is specified under *Start Location* options.

Specified Epochs

Converts the specified number of epochs, subject to the chosen starting point. You can also convert a specific time range that is based on GPS seconds of the week.



5.2.3.2 Recalculate Position and Time

If position records are requested when logging data, GrafNav's Raw GNSS Converter writes them to the GPB file. If no position records are logged, GrafNav's pre-processing functions will compute a single point C/A only solution during data conversion. This is done in order to plot the unprocessed trajectory to the Map window and, more importantly, is also used to determine whether ionospheric processing should be engaged.

GNSS ephemeris data is required should the pre-processing functions attempt to recalculate missing position records. If neither position records nor ephemeris data were requested when logging data, no position records will be written to the GPB file. If this is the case, recalculating position and clock data for a file can be done using this option. You may be required to load alternate ephemeris data (*File | Load Alternate Ephemeris*), should this be the reason no position data is present in your original file. See *Section 5.2.1.5, Load Alternate Ephemeris File* on page 142 for more information.

5.2.3.3 Add/Remove Cycle Slips...

This option should only be used for specialized testing reasons. GrafNav detects cycle slips through a combination of a flag decoded from the raw GNSS data (the carrier phase locktime value) and by a Doppler cycle slip check. Adding or removing cycle slips from the GPB viewer is thus not a commonly needed function.

5.2.3.4 Disable Satellite(s)

Disabling satellites is normally done within the *Satellite/Baseline Omissions* section of GrafNav's processing options. See *Satellite/Baseline Omissions* on page 45 for more information. This is the recommended method of ignoring satellite data as more options are available; including using time ranges and specifying if the satellite should be completely excluded or only excluded from ARTK or the fixed solution.

Disabling a satellite through the GPB viewer cannot be undone, unless a copy of the original GPB file was saved using *File | Save As*, or by re-decoding the raw GNSS data. This is another reason we recommend implementing any satellite omissions within GrafNav's processing options, as they can easily be removed later if required.

5.2.3.5 Recalculate Doppler

Missing or erroneous Doppler measurements are normally fixed automatically by the converter's pre-processing functions. Therefore recalculating Doppler

from the GPB Viewer is not a commonly needed function. Prior to version 8.40, when pre-processing functions were introduced, this feature was more commonly needed.

5.2.3.6 Edit Satellite Tracking L2C

As of January 2013, nine GPS satellites broadcast the L2C signal. This number has been gradually increasing since one satellite (PRN 17) began transmitting this signal in September 2005.

Should L2C tracking be enabled in your receiver, any satellites broadcasting L2C are decoded as such in the GPB file. The GPB Viewer displays a C2 identifier beside the PRN number of any L2C satellites.

Modifying which satellites track L2C is not generally required as this information is directly decoded in the raw GNSS data.

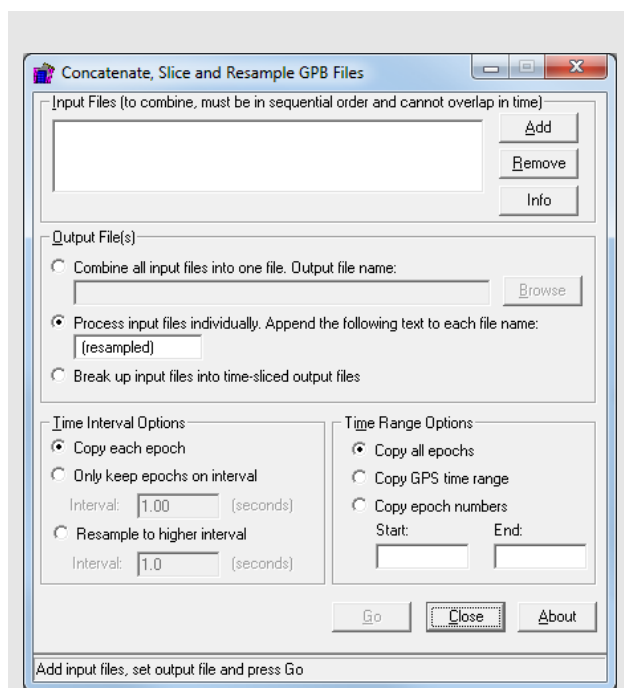
5.2.3.7 Edit L2C Phase Correction

L2C measurements are affected by an offset relative to L2 P/Y signals. This offset is dependent not only upon the manufacturer of your GNSS receiver, but also the firmware version used. GrafNav's raw GNSS converter applies a default L2C offset for each supported data type, however this may need to be adjusted for your specific receiver.

The correct L2C offset is needed in order to correctly resolve integer carrier phase ambiguities. If the incorrect L2C offset is applied, integer ambiguity resolution will fail even in ideal conditions. That is, even with a short distance between base and remote antenna, low multi-path and unobstructed tracking of all available GNSS satellites, correct ambiguity resolution becomes impossible.

GrafNav's RINEX converter applies a default L2C offset of 0 cycles, as it is common for some receiver manufacturers to remove the L2C offset during conversion to RINEX. If this is the case, measurements will be decoded as L2C (due to a flag set within the raw GNSS data), however the correction needs to be zeroed as it has already been removed by third party software.

If converting RINEX data that is known to contain a non-zero L2C offset, or any receiver which requires a different L2C offset than is applied by default, the correct value can be entered either during conversion (see the receivers global conversion options) or after conversion using this feature. There are four possible L2C offset values regardless of receiver manufacturer or firmware version: -0.25, 0.25, 0.5 or 0.



Time Interval Options

The three options are the following:

Copy each epoch

Select this if the data rate of the output file is to match that of the input file.

Only keep epochs on interval

Use this when a file is resampled to a lower data rate. The interval specified determines which epochs are copied into the output file.

Resample to higher interval

Use this when a file is resampled to a higher data rate.

✉ Resampling can only be performed on static data.

5.3 Concatenate, Slice and Resample Overview

This utility is available from *File | GPB Utilities*. This utility can be used to:

- Combine multiple GPB files from the same receiver into one. This could be used to combine multiple hourly observations into a larger file prior to processing.
- Resample static data to a higher interval (1 Hz to 10 Hz), or reduce the sampling rate of any file (static or kinematic) to a lower rate (10 Hz to 1 Hz).
- Produce multiple time sliced output files from one larger file (e.g. produce 24 individual hourly files from a single 24 hour file).

5.3.1 Concatenate, Slice and Resample GPB Files

Input Files

Use the *Add* button to locate the input GPB file(s). To concatenate several files, add them all at once as they will be automatically sorted chronologically.

Output File(s)

Determines how the creation and naming of new files is handled. For concatenating files, use the *Combine all Input Files into one file* option and provide a name for the output GPB file. For resampling or splicing multiple files, use the *Process Input Files individually* option. The name of the created output files depend on the name of their respective input file and the suffix that is specified. To break up a file into multiple files of *n* minutes, enable the *Break up input files into time sliced output files* option.

Time Interval Options

See the shaded box for descriptions of these options.

Time Range Options

Determines the range of time that is to be used for the creation of the new file. *Copy all epochs* is generally for resampling purposes. Splicing a file requires the selection of either *Copy Time Range* or *Copy Epoch Numbers*.

5.4 GNSS Data Converter Overview

This utility converts raw GNSS data into GPB format. Supported receiver formats are documented in *Section 5.4.3, Supported Receivers* on page 150.

5.4.1 Convert Raw GNSS data to GPB

Receiver Type

Choosing a receiver type prior to conversion applies a file filter commonly associated with the receiver type. This causes only files with these extensions to be listed under *Source Files* within the current folder. You may add or modify the default filter for any receiver type.

After pointing to the folder containing GNSS data to be converted, it is generally recommended to leave the receiver type as *Unknown/AutoDetect* and use either the *Auto Add All* or *Auto Add Recursively* functions.

Global Options

To view decoding options for individual receiver types, choose the receiver type from the pull down menu and then select *Global Options*. Any changes made to the global options are remembered and applied in the future.

You may wish to access the global options of a particular receiver in order to change the static/kinematic decoding preference or the default L2C offset.

Info

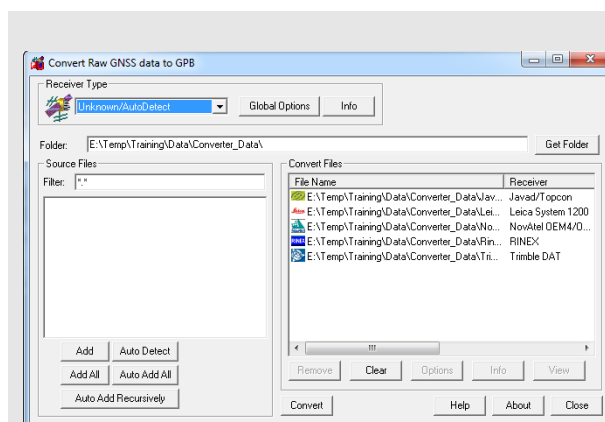
Provides information on the version and status of the DLL file used for the conversion.

Folder

Use the *Get Folder* button to browse to a folder containing raw GNSS data.

Source Files

Lists the files in the folder with extensions matching those specified in the *Filter* field. The options available here are listed in the shaded box.



Source file options

Add

When clicking *Add* after selecting an individual file under *Source files*, the converter attempts to auto-detect the receiver type if it has been left as *Unknown/AutoDetect*. If auto-detection succeeds, the file is added under the *Convert Files* section.

Add All

If a receiver type has been chosen from the pull down menu, all files are added for conversion under this receiver type. If *Unknown/AutoDetect* is selected as the receiver type, an auto-detection is performed on every file in the *Source Files* list.

Auto Detect

Auto-detects the selected file in the *Source Files* window for conversion.

Auto Add All

Auto-detects all the files in the *Source Files* list for conversion.

Auto Add Recursively

Auto-detects all files in the immediate folder and its subfolders. The maximum number of files that can be added is 256.

Convert Files

This lists all the files to be converted. The icon displayed to the left of the filename indicates the detected receiver type. Once the files have been converted, the icon changes to either a green check mark if conversion succeeds or a red X if conversion fails. Options available here including the following:

Remove

Removes the selected file from the *Convert Files* window.

Clear

Removes all files from the *Convert Files* window.

Options

Displays the options associated with the receiver type of the selected file. Any changes are only applied to the selected file and will not be retained.

Info

Displays the file path, receiver type and conversion status of the selected file.

View

Opens the converted GPB file within the GPB Viewer.

5.4.2 Pre-processing Checks

After conversion to GPB, pre-processing checks are performed in order to help ensure the file is ready for post-processing. Functions performed by the pre-processing checks include:

- Ensuring positions are present in the GPB file. If no position records have been requested during data logging, pre-processing computes a code only single point solution. This computed position is then written to the GPB file. GrafNav uses this position to display the unprocessed trajectory and determine whether ionospheric processing will be automatically engaged. The latter option depends on the scanned baseline distance prior to processing.
- Ensuring an accurate clock shift has been decoded to the GPB file. This is needed in order for GrafNav to correctly process and export results relative to GPS time. If this value is incorrect by a large amount it can result in gross processing errors.
- Automatic rejection of impossibly large or small pseudorange observations, which can occur due to unusual receiver signal tracking issues. Also automatically rejected are any duplicate PRN numbers (which will cause a processing failure), duplicate epochs and other unusual raw data problems.

- Computing missing Doppler measurements. A common issue with some RINEX data is that Doppler measurements are provided as 0 for the entire file. As GrafNav uses Doppler for cycle slip detection, this would result in large processing errors if it is uncorrected. Pre-processing checks ensure any missing Doppler measurements are recomputed from the C/A code.
- Static/Kinematic detection. The pre-processing checks attempt to set the static/kinematic flag appropriately. For surveys with significant position changes from epoch to epoch (such as would be the case for a kinematic survey) data is converted as *kinematic*. Conversely, if no significant movement is detected from epoch to epoch, portions of the data may be converted as *static*. The ability of the pre-processing check to reliably detect static data largely depends on the noise level of the unprocessed (or computed) position data.
- Processing environment detection. The unprocessed position records are scanned in order to determine if the dynamics are characteristic of aerial, ground vehicle or marine surveys. The detected environment is written to the header of the GPB file, which allows GrafNav to automatically load an appropriate processing profile (*GNSS Airborne*, *GNSS Ground Vehicle*, or *GNSS Marine*) the first time the processing dialog is accessed for a project.

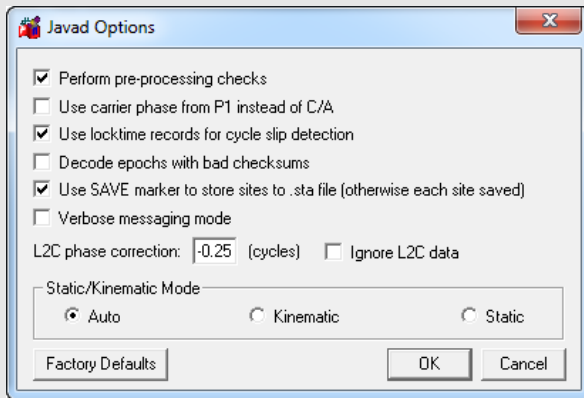


Table 15: Records Supported for Javad & Topcon

Record	Type	Comment
RC, rc	C/A Code Measurement Block	RC suggested.
1R	L1 P-Code Measurement Block	
3R	L2 C/A Code Measurement Block	
R2, r2, 2R, 2r	L2 P-Code Measurement Block	2R suggested.
PC, pc, CP, cp	L1 Phase Measurement Block	CP suggested.
P2, p2, 2P, 2p	L2 Phase Measurement Block	2P suggested.
3P, 3p	L2C Phase Measurement Block	
DC	L1 Doppler Measurements	Strongly recommended.
GE	GPS Ephemeris	Required.
NE	GLONASS Ephemeris	Required.
TO	Clock Offset	
TC	Locktime	
PO	Position	Recommended for GrafNet Users.
SI	PRN List	
RD	Receiver Date	

5.4.3 Supported Receivers

This section discusses the receivers that are currently supported by the *Raw GNSS Data to GPB* converter. This information includes the conversion options, as well as the supported formats and records for each receiver.

Javad and Topcon

- ☒ This converter supports GLONASS-enabled receivers.

Table 15, *Records Supported for Javad & Topcon* describes the supported records.

The following describes the options available for this converter:

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Use carrier phase from P1 instead of C/A

Measurements from P1 can be used instead, but this is not recommended.

Use locktime records for cycle slip detection

Locktimes from the Javad receiver are used instead of those computed by the decoder. Enable this if Javad locktimes are problematic.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. *Auto* is only used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags within the GPB file. If you wish to force the entire GPB file to be a certain mode, use the *Static* or *Kinematic* option.

Decode epochs with bad checksums

If disabled, epochs containing records with failed checksums will not be decoded. Otherwise, only the affected data is ignored.

Use SAVE marker to store sites to .sta file

Markers are saved to an STA file.

Verbose messaging mode

Alerts you of warnings and errors that have occurred.

L2C phase correction

If your receiver logs L2C measurements, then the phase offset must be entered. If you are unsure, you can disable its usage.

Leica System 500

This decoder handles data from the System 500 or SR530 receivers.

Table 16, Records Supported for Leica 500 describes the supported records.

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Re-compute position and receiver clock

Enable this option if the clock shift data is corrupt, or if positions records are not present. This option is not needed if pre-processing checks are enabled.

Combine multiple (.o00,.o01...) files into single GPB file

Leica SR530 receivers write all data into separate files from one session with different extensions. Enabling this option will combine files from one session into one GPB file

Use P1 carrier instead of CA carrier for L1 phase

Measurements from P1 can be used instead, but this is not recommended. Only available if Record #20 was logged.

Verbose message information output

Alerts you of additional warnings and errors that have occurred.

Scale L1 Doppler to L1 cycles

Recalculates Doppler to correct early Leica firmware bug.

Insert kinematic markers after gaps and stations

Ensures that static sessions are properly created.

Use new station format for output

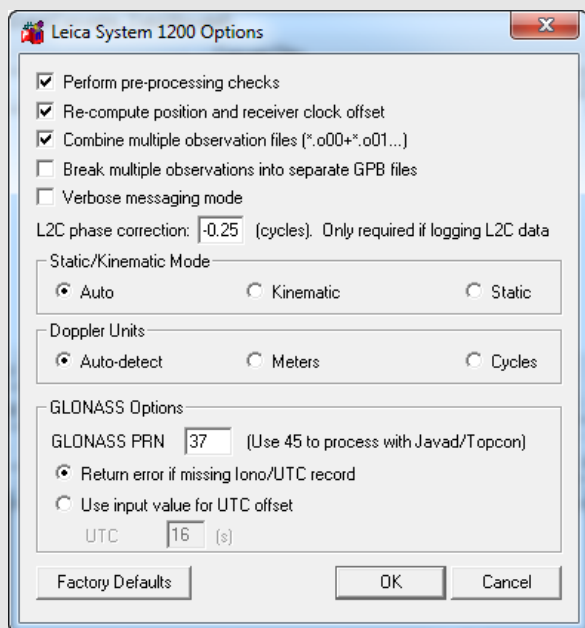
Utilizes a more-detailed format.

Use new GPB format

Converts data into the new GPB format.

Table 16: Records Supported for Leica 500

Record	Type	Comment
19	Measurements (compressed)	One of these records is required; record #20 needed if Doppler data is of interest.
20	Measurements (expanded)	
15	Ephemeris	Required.
10	Position	Recommended for GrafNet users.
13	Station/Event Mark	Written to STA file.
9	Antenna Height	Written to STA file.
108	Antenna Type	Written to STA file.

**Table 17: Records Supported for Leica 1200**

Record	Type	Comment
119	Measurements	One of these records is required, but #120 is recommended
120	Measurements	
115	Ephemeris	Required.
110	Position	Recommended for GrafNet users.
109	Antenna Height	Written to STA file.
113	Event Mark	Written to STA file.

Leica System 1200

Table 17, *Records Supported for Leica 1200* describes the supported records.

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Re-compute position and receiver clock offset

Enable this option if the clock shift data is corrupt, or if positions records are not present. This option is not needed if pre-processing checks are enabled

Combine multiple observation files

Leica receivers write data into separate files from one session with different extensions. This option combines files from one session into one GPB file

Verbose message mode

Alerts you of additional warnings and errors that have occurred.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. *Auto* is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the *Static* or *Kinematic* option.

Break multiple observations into separate GPB files

If you have logged data from multiple sessions and/or days, enable this option to create a separate GPB file for each.

Doppler Units

Some Leica firmware versions use different Doppler units. You can specify a unit, but we recommend that you rely on the decoder to automatically choose an appropriate unit.

GLONASS PRN

If you plan to process the data with a different brand of receiver, ensure that the GLONASS satellites are correctly numbered.

NavCom

Table 18, *Records Supported for NavCom* describes the supported records.

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. Auto is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the Static or Kinematic option.

Re-compute position and clock offset

Enable this option if the clock shift data is corrupt, or if positions records are not present. This option is not needed if pre-processing checks are enabled.

Report L2 cycle slips

Prints a message if an L2 cycle slip is encountered.

Verbose messaging mode

Allows you to see additional warning messages.

Table 18: Records Supported for NavCom

Record	Type	Comment
0xB0	Measurements	Required.
0x81	Ephemeris	Required.
0xB1	Position	Recommended for GrafNet users.
0xB4	Event Marker	Written to STA file.

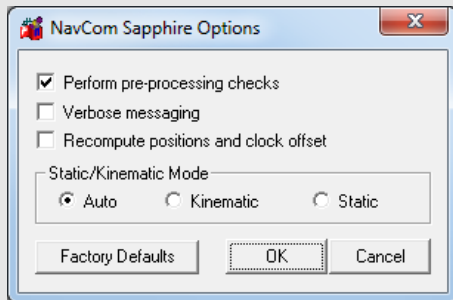


Table 19: Records Supported for NavCom Sapphire

Record	Type	Comment
MEAS1B	Measurements	Required.
EPHEM1B	Ephemeris	Required.
ALM1B	Almanacs	Required for GLONASS users.
PVT1B	Position	Recommended for GrafNet users.

NavCom Sapphire

Table 19, *Records Supported for NavCom Sapphire* describes the supported records.

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Verbose messaging

Alerts you of additional warnings and errors that have occurred.

Recompute positions and clock offset

Enable this option if the clock shift data is corrupt, or if positions records are not present. This option is not needed if pre-processing checks are enabled.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. Auto is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the Static or Kinematic option.

NovAtel CMC

This decoder handles data from the NovAtel CMC AllStar and SuperStar receivers. *Table 20, Records Supported for NovAtel CMC* describes the supported records.

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. *Auto* is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the *Static* or *Kinematic* option.

Verbose messaging mode

Displays additional warning messages.

Reject satellites with low CNO

Satellites with C/N0 values below the specified threshold will not be decoded. This option is not recommended.

Table 20: Records Supported for NovAtel CMC

Record	Type	Comment
ID #23	Measurements	One of these records is required, but ID #23 is strongly recommended over the others.
ID #13	Measurements (old style)	
ID #14	Measurements (old style)	
ID #15	Measurements (old style)	
ID #16	Measurements (old style)	Recommended for GrafNet users; should be requested last.
ID #20	Position	
ID #22	Ephemeris	Required.

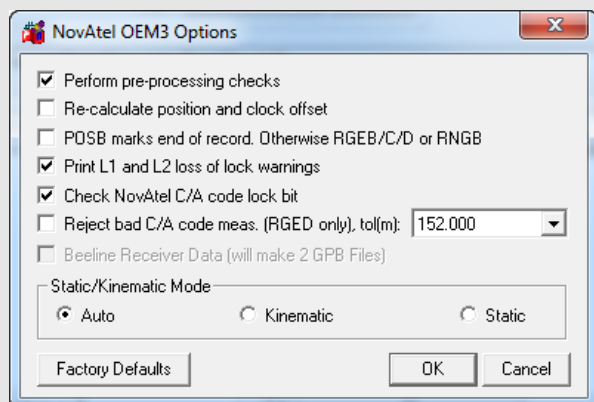


Table 21: Records and Files Supported for NovAtel OEM3

Record/File	Type	Comment
RGEb (ID #32)	Measurements (expanded)	One of these records is required, but RGED is recommended.
RGEc (ID #33)	Measurements (compressed)	
RGEd (ID #65)	Measurements (compressed)	
REPB (ID #14)	Ephemeris	Required.
POSB (ID# 01)	Position	Recommended for GrafNet users.
MKTb (ID# 04)	Event Mark (time only)	Written to STA file.
MKPb (ID # 05)	Event Mark (time and position)	Written to STA file.
CLKB (ID# 02)	Clock Information	See Notes .

- ✉ 1. If using receivers with standard correlators, you should either request the CLKB record, or else re-calculate the position and clock information. See the description of the decoder options on this page. The clock correction (offset) is needed for processing. This record is also suggested for users logging data right from power-up. Request the CLKB record before the measurement record.
2. Ensure that the baud rate is set high enough to properly handle 12 channels worth of measurement records, as well any additional records.
3. The GPS/GLONASS MiLLennium receiver has 24 channels.
4. Log MKTb or MKPb, but not both.

NovAtel OEM3

This decoder handles data from the NovAtel OEM3 receivers. *Table 21, Records and Files Supported for NovAtel OEM3* describes the supported records and files.

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. *Auto* is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the *Static* or *Kinematic* option.

Re-calculate position and clock offset

If there is no POSB record, use this option to re-calculate the position and time. This option is not needed if pre-processing checks are enabled.

-
- ✉ The REPB record must be present. Any epochs collected before the first REPB are not re-calculated. See *Section 5.2.3.2, Recalculate Position and Time* on page 144 for help correcting this.

To ensure enough ephemerides, the REPB record should be requested *ONCE* on start-up and *ONCHANGED* afterwards.

POSB marks the end of record

If the POSB record is requested after the measurement record, this option ensures that their time records match. Otherwise, request the measurement record last. This is only used when RTK or DGPS positions are to be preserved.

Print L1 and L2 loss of lock warnings

Alerts you of the losses of lock on carrier phase.

Check NovAtel C/A code lock bit

If the receiver flags a C/A code measurement as being bad, the entire measurement record is ignored.

Reject bad C/A code meas.

Applies only to the RGED record, where a code is used to indicate the range of values under which the standard deviation of the pseudorange measurement falls. This option uses this code to reject bad C/A code measurements.

NovAtel OEM4 / OEMV / OEM6

Table 22, *Records Supported for Novatel OEM4* describes the supported files.

-
- ☒ Almanac data can be used in *Mission Planner*. See *Section 2.8.11, Mission Planner* on page 91 for help.
-

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. *Auto* is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the *Static* or *Kinematic* option.

Re-compute position and clock offset

GrafNav requires valid clock shift data, while GrafNet requires position records. Enable this option if the clock shift data is corrupt, or if positions records are not present. This option is not needed if pre-processing checks are enabled.

Verbose messaging mode

Displays additional warning messages.

Create trajectory file (*.fsp) from following record

This option generates a separate FSP file for each supported position record that is logged. The files can be used to compare against the post-processed solution.

Create separate file for each MARKNTIME record

Enabling this option decodes the event marks from multiple inputs into separate station files.

GLONASS PRN Offset

Shifts the PRN number for GLONASS satellites. Offset must be greater than 32 to avoid conflict with the GPS constellation.

L2C phase correction

This correction value is inserted into the GPB header and can be used by the post-processing engine. OEMV firmware versions 3.0 and 3.1 use a correction of 0.50, while firmware versions 3.2 and later will use either -0.25 or 0.00. Generally, this value should occur on the $\frac{1}{4}$ cycle. See *Fixed Static* on page 54.

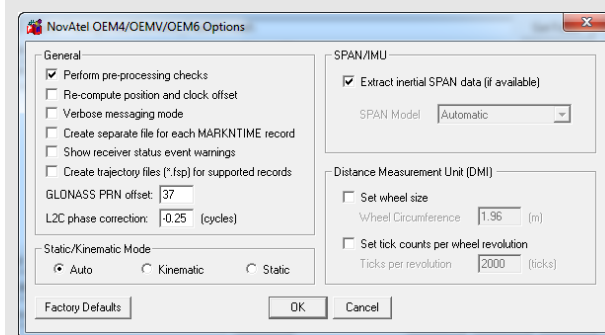


Table 22: Records Supported for Novatel OEM4

Record	Type	Comment
RANGEB (ID #43)	Measurements (expanded)	One of these records is required. Do not request both as it will result in duplicate epochs.
RANGECMPB (ID #140)	Measurements (compressed)	
RAWEPHEMB (ID #41)	Ephemeris	Required
GLOEPHEMERISB (ID #723)	GLONASS Ephemeris	Required if logging GLONASS data
ALMANACB (ID# 73)	Decoded Almanac	Optional. If present will be written to ephemeris (.epp) file. Can be used for Mission planning.
RAWALMB (ID #74)	Raw Almanac	
GLOALMANACB (ID #718)	GLONASS Almanac	
BESTPOSB (ID #42) RTKPOSB (ID #141) OMNIHPPOSB (ID #495) PSRPOSB (ID #47)	Position	BESTPOSB is recommended for GrafNet users
MARKTIMEB (ID #231)	Event Mark Time	Written to STA file
TIMEB (ID #101)	Receiver Time Information	
IONUTCB (ID #8)	Ionospheric Parameters	Optional. If present will be written to EPP file. This will be applied in single frequency processing but ignored in dual frequency processing.
GLOCLOCKB (ID #719)	GLONASS Clock Information	Optional for OEMV-3
RAWIMUSB (ID #325) RAWIMUSX (ID #1462)	IMU Measurements	SPAN users only. One of these records is required. Do not request both as it will result in duplicate epochs.
MARKnTIMEB (ID #1130, 616, 1075, 1076)	Event Mark Time	Written to STA file

(Sheet 1 of 2)

Table 22: Records Supported for Novatel OEM4

Record	Type	Comment
BESTLEVERARMB (ID #674)	IMU to GPS Lever Arm	SPAN users only. Allows lever arm to be automatically loaded in Inertial Explorer.
BESTGPSPOSB (ID #423) INSPVAB (ID #507) INSPVASB (ID #508) INSPOSB (ID #265) INSPOSSB (ID #321)	Position	SPAN users only
SETIMUTYPE (ID #569)	IMU Type	SPAN users only
MARKnPVAB (ID #1067, 1068, 1118, 1119)	Event Mark Time	Written to STA file
HEADINGB (ID #971)	Heading from dual antenna	Written to HMR file
SITEDEFB (ID #153)	Site definitions	
TIMEDWHEELDATAB (ID #622)	Odometer Measurements	SPAN users only. Written to DMR file.
WHEELSIZEB (ID #646)	Circumference of Wheel	SPAN users only. Written to DMR file.
(Sheet 2 of 2)		

Inertial Decoding Options***Extract inertial SPAN data***

This option is only for users of NovAtel's SPAN Technology and is only available in Inertial Explorer. Refer to *Inertial Explorer Version 8.50 Manual* for details.

RINEX

Receiver Independent Exchange (RINEX) data is a standard, manufacturer independent ASCII format for raw GNSS data. All GNSS manufacturers should provide tools to convert their native data to RINEX format. If your receiver type is not directly supported by GrafNav, first convert the data to RINEX using a utility supplied by the manufacturer and then import the RINEX data to GrafNav.

The following describes the options available for this converter:

General Options

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. *Auto* is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the *Static* or *Kinematic* option.

Advanced Options

GLONASS PRN offset

Shifts the PRN number for GLONASS satellites. Offset must be greater than 32 to avoid conflict with the GPS constellation.

L2C phase correction

If the RINEX file contains L2C measurements, then the phase offset must be set.

Shift time to user interval

The decoder will attempt to determine the data interval by reading the header or scanning the observation file. If this fails, enable this option to force an interval.

Doppler Source

These options allow you to choose a method of obtaining Doppler measurements.

Automatic/use D1 value

Uses the D1 value, if present, from the RINEX file for Doppler. Otherwise, it uses *Calculate from CA code* for data intervals of 10 seconds or less, and *Use ephemeris (static)* for anything else.

Calculate from L1 phase

Select this option if the Doppler signal is missing or unstable.

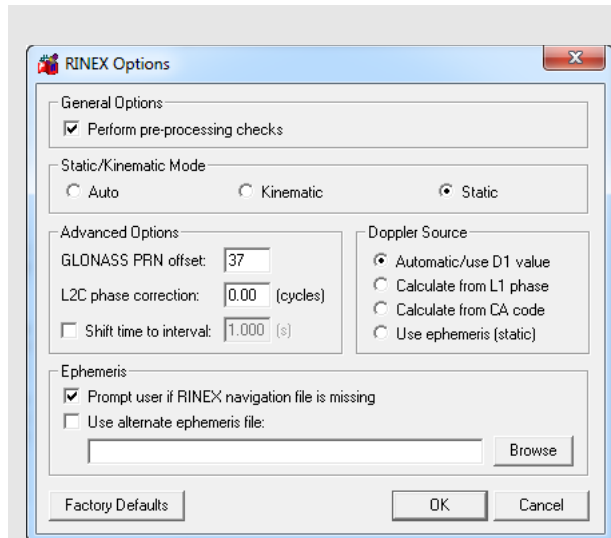


Table 23: Files Supported for RINEX

File	Type	Comment
*.yyo, *.obs, *.rxo	Measurements	One of these files is required.
*.yyd	Measurements (compressed)	
*.yyh, *.nav, *.rxn	GPS Ephemeris	Required.
*.yyg	GLONASS Ephemeris	

- ☒ The yy in the file extensions found in the table above designate the last two digits of the year that the observations were collected in.

Calculate from CA code

If the Doppler signal is missing or unstable, using the CA code will create fewer problems than using L1 phase, but velocity accuracies may be worse.

Use ephemeris (static)

Assumes static data and computes Doppler from satellite velocities.

Ephemeris***Prompt user if RINEX Nav file is missing***

If a navigation file is either missing or has a different name than the observation file, you will be prompted to select a navigation file.

Use alternative ephemeris file

You may define a path to the navigation file manually. This will override the previous option.

RTCM Version 3.0

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Re-compute position and clock offset

GrafNav requires valid clock shift data, while GrafNet requires position records. Enable this option if the clock shift data is corrupt, or if position records are not present. This option is not needed if pre-processing checks are enabled.

Verbose messaging mode

Displays additional warning messages.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. *Auto* is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the *Static* or *Kinematic* option.

GLONASS PRN offset

Shifts the PRN numbers for GLONASS satellites. Offset must be greater than 32 to avoid conflict with the GPS constellation.

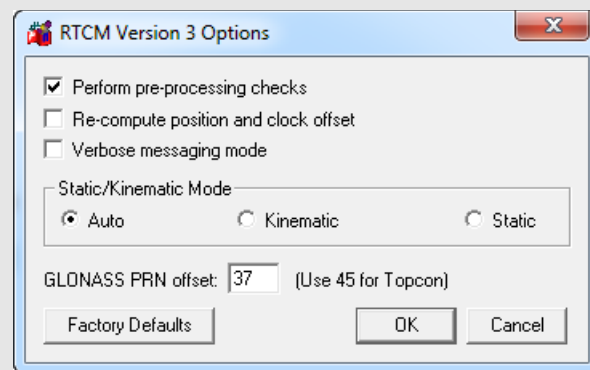


Table 24: Records Supported for RTCM Version 3

Record	Type	Comment
1002	L1 only measurement	One of these records is required, depending on the receiver's capabilities
1004	L1/L2 measurements	
1010	GLONASS L1 only measurements	If working with GLONASS, then one of these records is required, depending on the receiver's capabilities
1012	GLONASS L1/L2 measurements	
1019	GPS Ephemeris	Required
1020	GLONASS Ephemeris	Required for GLONASS users

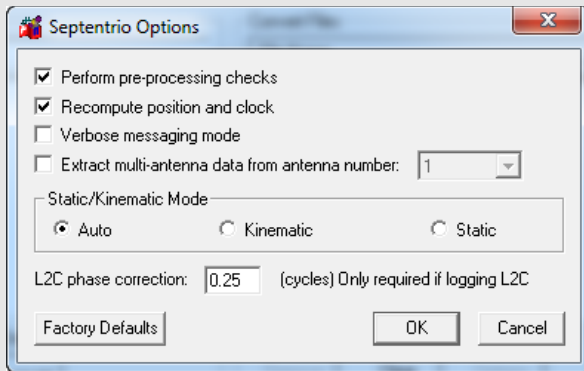


Table 25: Records Supported for Septentrio SBF

Record	Type	Comment
5889	Measurements	One of these records is required
5890	Measurements (compressed)	
5891	Ephemeris	Required
5904	Position	Recommended for GrafNet users
5924	Event	Written to STA file

Septentrio SBF

Table 25, *Records Supported for Septentrio SBF* describes the records supported.

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Re-compute position and clock

GrafNav requires valid clock shift data, while GrafNet requires position records. Enable this option if the clock shift data is corrupt, or if positions records are not present. This option is not needed if pre-processing checks are enabled.

Verbose messaging mode

Allows you to see additional warning messages.

Extract multi-antenna data

For multi-antenna applications only.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. *Auto* is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the *Static* or *Kinematic* option.

Thales/Ashtech/Magellan B-File

This decoder handles Thales data that has been downloaded using the Thales utility. Log this data into internal receiver memory. *Table 26, Files Supported for Thales B-File* describes the supported files.

Thales (Ashtech) Receiver Type

Selects the receiver used to collect the data. If auto-detect does not work, then select the receiver manually.

General Options

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Re-calculate position and clock offset

Enable this option if the clock shift data is corrupt, if position records are not present or if many cycle slips exist. This option is not needed if pre-processing is enabled.

Detect static/kinematic from site name

Looks in B-file for data tagged as static or kinematic, using ??? site ID.

Ignore questionable L2 phase

Allows for processing of highest quality L2 data only. Should be enabled if ARTK is having difficulties.

Verbose messaging mode

Allows you to see additional warning messages.

Extract stations information from Ashtech 'D-File'

Various Thales hand-held controllers output a D-file containing features and antenna height information. Enable this checkbox to utilize this information.

Ignore SBAS Satellites

Newer versions of Thales firmware have resulted in the logging of raw data from SBAS satellites, which are not supported by the software. As such, this option should be left enabled to ensure the data is not written to the GPB file.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. *Auto* is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the *Static* or *Kinematic* option.

Table 26: Files Supported for Thales B-File

File	Type	Comment
BssssAyy.jjj	Measurements	Required.
EssssAyy.jjj	Ephemeris	Required.
SssssAyy.jjj	Static Station Information	Written to STA file.
DssssAyy.jjj	Kinematic Station Information	Written to STA file.
PHOTO.DAT	Event Mark	Read in directly by software.

- ✉ Thales files follow a strict naming convention. In the table above, *ssss* is the site name, *yy* is the last two digits of the year, and *jjj* is the day of the year.

Antenna heights may need to be edited within the feature editor if not kept constant, as the Thales format only allows for one value.

You might need to select the receiver type manually.

UTC Options***Use the following UTC time***

Changes the GPS to UTC time offset from the current nominal value to user-defined value. Normally used for GLONASS processing if no UTC is contained in the data.

Correct GPS time in D-FILE for UTC offset

D-files can have GPS or UTC time. This option changes time from UTC to GPS.

Dfile Options***Chain Repeated Station Marks into 1 Static Session***

Combines sessions that are repeated in the Seismark software into one session.

Do NOT Chain Marks that are more than n seconds apart

This value controls the time tolerance used in the previous setting. If two static periods are marked less than the amount apart, they will be combined.

Thales/Ashtech/Magellan Real-Time

This decoder converts Thales Real-Time (DG16, G12, or Super C/A) data. The real-time data forms when data is logged externally from the receiver using a custom data logger. *Table 27, Records Supported for Thales Real-Time* describes the supported records.

General Options

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Recompute position and time

Enable this option if the clock shift data is corrupt, or if positions records are not present. This option is not required if pre-processing checks are enabled.

Decode MACM messages and ignore others

If both MBN/MCA and MACM records exist, only the MACM will be decoded.

Decode old-style MBN locktime

Some older units (for example, Sensor II) output locktimes with a different resolution. Enable this option to output the locktime value.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. *Auto* is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the *Static* or *Kinematic* option.

Parthus MACM Settings

These settings are for logging MACM records:

Decode Parthus style MACM record

Parthus units (NS100, GSU-1, and GSU-2) utilize the MACM record. However, due to timing differences, its implementation is not compatible. Therefore, enable this option.

Data interval adjustment

The GSU-1 benefits greatly by having the correct data interval entered, while the GSU-2 is best processed using the raw time and having the base interpolated onto these times. See *Section 5.3.1, Concatenate, Slice and Resample GPB Files* on page 146 for help.

Table 27: Records Supported for Thales Real-Time

Record	Type	Comment
MBN	Measurements	One of these records is required; see Note 1
MCA	Measurements	
MPC	Measurements	
MCL	Measurements	
MACM	Measurements	
ITA	Measurements (C/A Code Only)	
CT1	Measurements (C/A Code Only)	
CT2	Measurements (C/A Code and L1 Phase)	
CT3	Measurements (C/A Code, L1 Phase and C/A Code)	
SNV	Ephemeris	Required.
SNG	Ephemeris (GLONASS)	Required for GLONASS users.
PBN	Position	See Note 2 .

- ✉ 1. The MBN or MACM records are recommended for G12 receivers. The MACM record is designed for high-speed data output that is, 10Hz or 20Hz, under limited bandwidth conditions. The ITA record is for G8 receivers, while the MPC is for dual frequency receivers, such as those in the Z-series. The MCL record is an L2 codeless record.
2. Marks the end of the record. Recommended for GrafNet users.

UTC Offset for GLONASS decoding

The following option is available for those users logging GLONASS measurements:

Use the following UTC offset for decoding

Allows you to define your own UTC offset rather than using the nominal or detected value. Important for GLONASS processing.

Alternate Ephemeris***Use alternate ephemeris***

Enable this option if ephemeris data is missing (for example, Parthus, GSU-2) to specify an outside EPP file.

Thales/Ashtech/Magellan DNSP

Table 28, *Records Supported for Thales DNSP* describes the supported records.

-
- ☒ The Measurement Q record includes the receiver time record, while the Measurement R record includes the satellite time record. As such, the former is recommended.
-

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. *Auto* is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the *Static* or *Kinematic* option.

Table 28: Records Supported for Thales DNSP

Record	Type	Comment
Measurement Q (hex 51)	Measurements	One of these records is required;
Measurement R (hex 52)	Measurements	
Measurement E (hex 45)	Ephemeris	Required.

Table 29: Files Supported for Trimble DAT

File	Type	Comment
*.dat	Measurements, Ephemeris and Event Marks	Required.

Trimble DAT

This decoder converts data from Trimble 4000-5800 receivers. The Trimble data files (DAT) are formed when data is logged internally in the receiver.

The *Table 29, Files Supported for Trimble DAT* describes the supported files.

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. *Auto* is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the *Static* or *Kinematic* option.

Recompute position and clock offset

Enable this option if the clock shift data is corrupt, or if positions records are not present. This option is not needed if pre-processing checks are enabled.

-
- ☒ The antenna height extracted by the decoder may be the slant distance.

Trimble SSF files cannot be directly decoded using this utility. As such, they must be converted to DAT or RINEX format first.

Trimble Real-Time

Data captured directly from a Trimble 4000-5800 receiver can also be converted to GPB using this decoder.

The *Table 30, Records Supported for Trimble Real-Time* describes the records supported.

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. *Auto* is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the *Static* or *Kinematic* option.

Verbose messaging mode

Displays additional warning messages.

Table 30: Records Supported for Trimble Real-Time

Record	Type	Comment
0x0	Measurement	Required.
0x1	Position	Recommended for GrafNet users.
0x2	Ephemeris	Required.

Table 31: Records Supported for U-Blox

Record	Type	Comment
ID #10	Measurements	Required.
ID #31	Ephemeris	Required.
ID #02	Position	Recommended for GrafNet users.
ID #22	Clock Information	Recommended.

U-Blox

Table 31, *Records Supported for U-Blox* describes the supported records.

Perform pre-processing checks

If enabled, data is scanned after conversion to correct potential issues. See *Section 5.4.2, Pre-processing Checks* on page 148 for more information.

Static/Kinematic Mode

This option controls how the static/kinematic flags are set in the final GPB file. *Auto* is used in conjunction with the pre-processing checks. It attempts to automatically set the flag based on the computed dynamics. This could result in a mixture of static/kinematic flags in the GPB file. If you want to force the entire GPB file to a specific mode, use the *Static* or *Kinematic* option.

Recompute position and time

GrafNav requires valid clock shift data, while GrafNet requires position records. Enable this option if the clock shift data is corrupt, or if positions records are not present. This option is not needed if pre-processing checks are enabled.

Verbose messaging mode

Displays additional warning messages.

Table 3: List of Output Variables

Variable	Description
Absolute ECEF-XYZ	XYZ coordinates in the Earth Centred Earth Fixed Frame which is a Cartesian frame centred at the ellipsoid origin
Ambiguity Drift	Drift on ambiguities over time; low ambiguities indicate stable solution
Antenna Height	Height of the pole or tripod above the station marker
Azimuth (1 \diamond 2)	Angle between true north and the baseline made from between FROM and TO stations
Azimuth (2 \diamond 1)	Angle between true north and the baseline made from between TO and FROM stations
Body Frame Acceleration - XYZ	Acceleration components in the vehicle body frame
Body Frame Velocity - XYZ	Velocity components in the vehicle body frame
Azimuth StdDev	Estimated error of the computed azimuth.
British-East, North	East and North coordinates in the British State Plane projection
C/A RMS	Root mean square of C/A code signal
Checksum (8-bit)	The absolute value calculated by using XOR, ADD, or NMEA methodology on the 8 data bits of each character in the sentence; decimal and hexadecimal formats may be selected (user will be prompted for these options after the profile is created)
Combined Scale Factor	Scale factor used by surveyors. It applies the map scale factor combined with the ellipsoidal height correction, which can be used to scale distances on the ellipsoid to the earth's surface.
Combined Standard Deviation	Combines east, north, up position standard deviations into one value. Same value is written by Write Coordinates.
Computed Azimuth	Azimuth from base antenna to remote antenna in moving baseline projects.
Convergence	Meridian convergence for the current location in the current map projection
Corrected GPS Time	GPS time corrected for receiver clock bias
Course Over Ground	Direction of travel indicated by velocity vector.
Date	Date of the epoch or feature
Description	Description of the station or feature from the STA file
Distance Error (Azimuth)	Error in the computed baseline length in moving baseline projects.
Double Difference DOP	Double Difference DOP which is approximately equivalent to PDOP ²
East, North, Height Fwd/Rev Separations	Separations between the forward and reverse solution in the east, north, and height axes
East, North, Height Fwd/Rev RMS	Root mean square of the separations between the forward and reverse solution in the east, north, and height axes
East, North, Up Standard Deviations	Estimated east, north up position standard deviations in the local level frame
East, North, Up Velocities	East, North, Up velocity components in the local level frame
East, North, Up Velocity Standard Deviations	Estimated east, north up velocity standard deviations in the local level frame
East, North, Up Offset Applied	When a 3-D offset is applied to camera event marks, this field can be used to verify that the proper offset is applied. This offset is oriented to local level that is, true-north.
ECEF Covariance Matrix	Estimated ECEF position covariance matrix; needs extended output in GrafNav
ECEF Vector XYZ	XYZ components of the vector between base and remote in the ECEF frame

Table 3: List of Output Variables (continued)

ECEF Velocity Covariance Matrix	Estimated ECEF velocity covariance matrix; needs extended output in GrafNav
ECEF XYZ Standard Deviations	Estimated ECEF position standard deviations in the XYZ axes; needs extended output in GrafNav
ECEF XYZ Velocities	XYZ velocity components in the ECEF frame
ECEF XYZ Velocity Standard Deviations	Estimated ECEF velocity standard deviations in the XYZ axes; needs extended output in GrafNav
Ellipsoidal Height	Height above current ellipsoid; based on datum selected during processing
Ellipsoidal Height Scale Factor	Used to scale distances on the ellipsoid to the earth's surface.
End Time	End time of the static session
Error Ellipse Orientation	Orientation of the error ellipse (theta)
Error Ellipse Semi-Major	Estimated error along the semi-major axis of the error ellipse (a)
Error Ellipse Semi-Minor	Estimated error along the semi-minor axis of the error ellipse (b)
Extended Ambiguity Status	Indicates if KAR fixed the ambiguities.
Field Separator	User can select what character separates each variable in a record
Fixed Reliability	Reliability number for fixed static solutions
Float/Fixed Ambiguity Status	Indicates if KAR fixed the ambiguities. Also available in GrafNet.
Gauss Kruger-East, North	East and North coordinates in the Gauss Kruger projection
Geoidal Undulation	Height of the ellipsoid above or below the geoid (user will be prompted with options after profile creation)
GLONASS/GPS Time Offset	Time difference between GPS and GLONASS expressed in meters
GLONASS/GPS Time Offset Stdev.	Standard deviation of the time difference between GPS and GLONASS expressed in meters
GPS Corrected Time	Exact time of measurement in the GPS time frame.
GPS Course-over-ground (track)	Direction of travel computed from trajectory (velocity)
GPS Time/Date	Time of the epoch or feature; time format may be changed to user's preference
GPS Week Number	Week number for GPS data starting from January 4, 1980; Depending in the format, this week number may or may not reset after 1023
Heading Angle	Negative yaw (see IMU angle definition).
Height Difference	Vertical height difference between stations
Height Error Estimate	Estimated error along the vertical axis (dh)
Horizontal Distance	Horizontal distance on the ellipsoid between stations (geodesic)
Horizontal Standard Deviation	Estimated position standard deviation in the east and north axes of a local level frame
Irish-East, North	East and North coordinates in the Irish State Plane projection
L1 Doppler RMS	Root mean square of L1 Doppler signal; useful for INS integration
L1 RMS	L1, or Iono-free root mean square
Lambert-East, North	East and North coordinates in the Lambert Conformal projection
Latitude	North/South geographic coordinate
Local Level Covariance Matrix	Estimated local level position covariance matrix; needs extended output in GrafNav

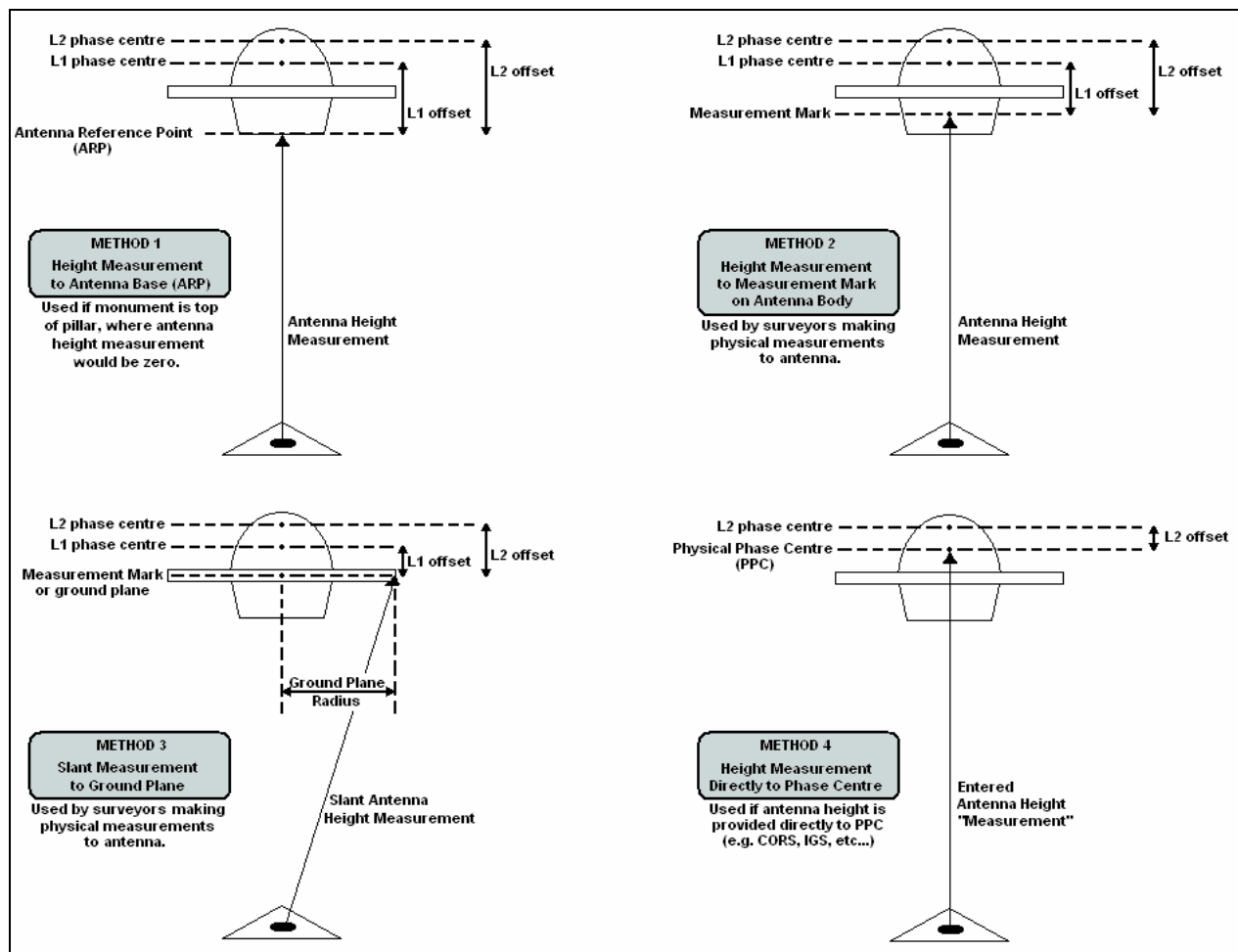
Table 3: List of Output Variables (continued)

Local Level Velocity Covariance Matrix	Estimated local level velocity covariance matrix; needs extended output in GrafNav
Local Level XYZ	Local level left hand side frame where the x axis is pointing east, the y axis is pointing north and the z axis is pointing up; the frame is centred at the master station
Local Plane XYZ	XYZ axes of a coordinate frame defined by two or more points (see local plane options)
Local Time/Date	GPS time and date with time-zone offset applied
Longitude	East/West geographic coordinate
Map Scale Factor	Map projection scale computed for a location
Master File Name	Name of Master GPB file
Num Fwd+Rev or Comb Baselines	Number of baselines used in the combined solution.
Num GLONASS satellites	Number of GLONASS satellites
Num GPS satellites	Number of GPS satellites
Number of Satellites	Total number of GPS and GLONASS satellites
Orthometric Height	Height above the geoid (mean sea level height)
PDOP, HDOP, VDOP	Position dilution of precision, horizontal position dilution of precision and vertical DOP. May be slightly different than values from other sources due to the differential computation
Pitch Angle	IMU pitch angle (see IMU angle definition)
Project Name	Name of current project
P2 RMS	Root mean square of P2 code signal
Quality Number	Quality factor from GrafNav; 1 (best) to 6 (worst)
Relative Azimuth	Azimuth between current and previous feature or epoch.
Relative Height Difference	Relative height difference between current and previous epochs or features
Relative Horizontal Distance	Uncorrected horizontal distance on the ellipsoid between the current and previous epochs. Multiply by Combined Scale Factor to bring to mapping plane and surface
Relative Slope Distance	Free-air distance between neighboring epochs or features. Distance between current and previous.
Remarks	Remarks of the station or feature from the STA file
Remote File Name	Name of Remote GPB file
Roll Angle	IMU roll angle (see IMU angle definition)
Roll, Pitch, Heading Separation	The difference between the combined solutions in terms of Roll, Pitch, and Heading.
Roll, Pitch, Heading StdDev	Estimated attitude accuracy.
Scale Factor	Horizontal distance ratio between the globe and the map distance for the current point in the current map projection
Selectable Grid	Allows user to enter a north and east value for a user defined grid. Grids can be modified and added using the Grid Manager (see Tools Menu).
Sequence Number	Allows the user to number epochs in the data with a user defined start and end sequence number, as well as, an incremental value
Slope Distance	Free air distance between stations
Solution Type	Type of solution used. In GrafNav, possible solution types include SF-Carrier, DF-Carrier, IonoFree, Rellono, CaOnly, SingPoint. In GrafNet, FixedSoln, FloatSoln.
Standard Dev. (NO PPM)	Trace of the covariance matrix expressed as a standard deviation; no distance dependent errors included

Table 3: List of Output Variables (continued)

Start Time	Start time of the static session
State Plane-East, North	East and North coordinates in the US State Plane projection
Static/Kinematic Status	Indicates if an epoch is static or kinematic
Station Name	Name describing the station, feature or camera mark
Surface Distance	Horizontal distance between the two stations on the surface (corrected geodesic)
Sun Angle	Angle of the sun above the horizon.
Time Length	Time length of the static session
TM-East, North	East and North coordinates in the Transverse Mercator projection
Total Slope Distance	Spatial distance between two points
Total Horizontal Distance	The shortest path between two points on the surface of a sphere (for example, Great circle)
Transformed Grid	Allows for scaling, rotating and translating of a selectable grid.
User Text String	String of text defined by user
UTC Corrected Time	Same as UTC Time, but a correction for the receiver clock bias is applied. This is the most precise time. Only applicable for epochs.
UTC Date	Date in UTC time.
UTC Time	Time which is available in various format. This is the epochs or feature time offset from GPS seconds by the GPS-UTC time offset. This time is uncorrected for the receiver clock bias
UTM-East, North	East and North coordinates in the Universal Transverse Mercator projection
VSF Ellipsoidal Height	Ellipsoidal height corrected by the map scale factor
VSF Orthometric Height	Orthometric height corrected by the map scale factor. Used in photogrammetry applications to create an elevation that is more compatible with measured ground coordinates
XYZ Accelerometer Bias	This is the apparent output in acceleration when there is no input acceleration present. It is computed by the GPS/INS Kalman filter and the effects may be sinusoidal or random.
XYZ Gyro Drift	This is the apparent change in angular rate over a period of time. It is computed by the GPS/INS Kalman filter and the effects are usually random.

Figure 1: Antenna Measurements



The following lists the available commands and a short description of their usage. The required format, status, and a description of each command is given. Any subset of the following may be used for the user's particular input file. User commands can also be observed via *Settings | Individual | User Defined* in GrafNav. Note that any spaces in file names, datum names, and so on, are substituted in the configuration file with an asterisk (*).

ALT_FILE = fname EPP/SP3/CLK/IONEX ENABLE/DISABLE

This specifies the alternate ephemeris file (.epp file), or precise ephemeris (.sp3), or IONEX file (.yyI), or Satellite Clock file (.clk). They are set to ENABLE once added to the project. DISABLE will disable the processor from using the file.

APPLY_ANT = ON/OFF

Set to ON if elevation based antenna corrections are to be employed. Note that an antenna profile must also be specified for master and/or remote receivers. This is ON by default; use OFF to disable antenna correction.

AZ_DETERM = ON/OFF Dist DistSD

Moving baseline projects only. Used to enable azimuth computation using an antenna distance constraint. Distance and standard deviation are in meters. Typical standard deviations are 2-3 cm.

BASE_SAT = sv_num

Satellite PRN number of base satellite used for differenced computations. Normally, this value should be left at 99, which will cause the program to automatically choose the best satellite using a number of criteria. The default value is 99.

CYCLE_TEST = mode

This can be LOCKTIME, DOPPLER, or BOTH, and determines the manner in which cycle slips are detected in kinematic mode. In general, either BOTH or DOPPLER should be used. Basically, using DOPPLER will disable LOCKTIME check.

CYCLE_TOL = tol

Tolerance used to detect cycle slips on the L1 phase in kinematic mode. These tolerances generally vary from 1 - 500 cycles, and depend on receiver type, vehicle dynamics and type of Doppler. Numerous cycle slips reported may indicate that CYCLE_TOL is too low. A value of 0.0 will cause cycle slip tolerance to be computed automatically from data interval. This value is also subsequently multiplied by 30 [default is 0.0].

DATUM = ProcDatum [Wgs84Conv]

This is the datum that processing is to be performed in, and the satellite coordinates are transformed into this datum. See GrafNav for a list of available datums. WGS84Conv is the conversion to be used. Use WGS84Conv=AUTO to allow NGPS32.DLL to select the best datum. Note that datums are read from manufact.dtm and user.dtm located in the same directory as the DLL.

DETAILED_SUM = ON/OFF

ON if detailed parameter info is to be printed at the start of the static/kar summary (.fss/rss) file.

DOP_TOL = dd_dop_tol

Epochs with DD_DOP above this value are not printed to .FWD/REV files as the geometry is deemed too poor. Default value is 100.0.

DOPPLER_TOL = tol

No longer supported.

DUAL_FREQUENCY = on/off on/off off/relative/free on/off/smoothed OFF/ON

Use P-code for long baseline processing. No longer used; see USE_PCODE command.

OFF/ON - Use L2 phase for ambiguity resolution (should be ON).

OFF/RELATIVE/FREE – Use relative ionospheric correction or long baseline L3 iono-free baseline processing

ON/OFF/SMOOTHED – Apply ionospheric correction to C/A.

SMOOTHED applies a low pass filter to the raw ionospheric corrections before implementing them.

DYNAMICS = EnableFlag DynFlag

This parameter controls the vehicle dynamics model that can be employed in the Kalman filter. EnableFlag=ON/OFF/AUTO, while DynFlag=LOW/MEDIUM/HIGH. Generally AUTO should be used, which means that dynamics constraint is off if Doppler is employed or ON if no Doppler is used. If ON, HIGH dynamics is used. If ON, use DynFlag to set vehicle dynamics.

ELEV_MASK = angle

Cut-of elevation for excluding satellites from the computations. This value is expressed in degrees. This elevation mask value may have to be increased to 15 degrees or more in high multi-path environments or during ionospheric storms. Some data tracked under 10 degrees may exhibit noise characteristics. Default value is 10.0.

FF_DOP_TOL = dop_tol

DD_DOP Tolerance over which a fixed integer solution is deemed “float”. Allows user to control how easily a fixed changes to a float solution. Does not affect processing. Default is 25.

FIX_AUTO = Min DtL2 MaxLenL2 MinDtL1 MaxDtL1 ON/OFF

Controls automatic fixed static solution usage on static sessions. Use ‘ON’ to enable, or “OFF” to always use. Note that fixed static must also be enabled in processing settings. MinDt is minimum time length in seconds while MaxLen is maximum allowable distance in km.

FIX_CORRECT_SLIP = ON/OFF

ON if whole cycle slips are to be corrected forming a continuous phase in fixed solution. By default this option is ON.

FIX_CUBE = mode L1User L2User

Mode is AUTOREDUCE, NORMAL, or USER. Sets the search region size for fixed solution. L1User and L2User are the sizes of the search area to be used for USER mode. Default is NORMAL. AUTOREDUCE often works very well.

FIX_INTERVAL = DataInterval

Data interval in seconds to use for fixed static processing. Default is 15 seconds.

FIX_IONO_DIST = dist

Used in the AUTO fixed solution L2 model for deciding between IONO and NORMAL L2 noise models. dist is in kilometers. Default is 5 km.

FIX_L2_NOISE = IONO/NORMAL/AUTO

Selects L2 noise model for processing fixed solution. IONO performs iono correction, NORMAL does not, AUTO selects between the two based on the FIXED_IONO_DIST command.

HGT_MODEL = EstFlg KalFlg KarFlg ZOff/USEHI HgtSd [KarTol]

Controls DEM height constraint (Sportvision version only!)

EstFlag = NAV / ALL / OFF

Kar/KalFlag = ON / OFF

INITEX = type time snap dir window size stdev anthgt phi lamda ht
[[staname or ss_index] anthgt ELL/ORTHO]

Used to set the remote position at a given location.

INTERVAL = DataInterval

This specifies the processing interval in seconds. It should be equal to or greater than the recording interval for proper time length computations. If this value is larger than the recording interval, then this new value will be used for processing. Use 0.0 to process all epochs. The default value is 0.0.

IONO_DIST = dist_in_km

Baseline distance in km at which relative iono-free processing will begin. Default is 5 km.

IONO_PPM_TOL = tol

Reject KAR or fixed static solutions if computed ionospheric error is greater than tol in PPM. Default value is 10 PPM. This setting is not in GrafNav's dialogue boxes.

ISSUE_KAR_DIST = ON/OFF DistKm1 DistKm2

This will engage KAR on first occurrence of dist < dist1 and reset the distance check when dist > dist2.

ISSUE_KAR_DOP = ON/OFF doptol

Engage KAR every time DD_DOP goes above doptol.

ISSUE_KAR_TIME = ON/OFF NumMin

Engage KAR every 'NumMin' minutes.

KAR_COV_L2 = ON/OFF sf offset

Determines KAR search area using ambiguity variances. Search area is computed to be SearchArea= \pm sf*AmbVar + offset. This option only works for dual frequency processing.

KAR_CUBE = cube_size_l1 cube_size_l2

Size of kinematic ambiguity resolution (KAR) search cube in meters. A cube \pm cube_size/2 will be searched from the initial approximate position, which is obtained from the program following the loss of lock. The default value is 2.0 m. This value should be increased if it is suspected that the remote position is outside of the search cube. However, larger values increase the possibility of an incorrect intersection found.

KAR_DISTANCE = l1_dist l2_dist

Do not engage KAR if distance is greater than value. Distances are defined in km. After KAR is engaged, it will search farther. Use KAR_USE_DIST to prevent KAR from utilizing data past a certain distance.

KAR_ELEV_MODEL = ON/OFF

Default is ON. KAR uses the KAR_TWOSTAGE_SAT highest satellites for its ambiguity search.

KAR_EPOCH_FILTER = epoch_size

Interval between storing epochs for KAR. epoch_size specified in seconds. This controls how much data KAR will use.

KAR_EPOCH_SIZE = epochs_l1 epochs_l2

Number of epochs between KAR ambiguity searches if L1 only or L1/L2. This controls how often KAR will search.

KAR_EXACT_INTERVAL = ON/OFF

Only use epochs exactly on KAR_EPOCH_FILTER in KAR.

KAR_FAST = ON/OFF

ON to enable 'Fast KAR'

KAR_IONO_DIST = dist_in_km

Used in auto L2 noise model for choosing between HIGH and IONO.

KAR_L2_NOISE = AUTO/HIGH/IONO/MEDIUM/LOW

Model used for KAR L1/L2 ambiguity search. Default is AUTO.

KAR_MAX_DOP = 7.0

Tolerance for allowable DOP during a KAR solution. Default is 9.0.

KAR_MAX_TIME = 30

After this number of minutes, KAR will restart searching

KAR_MB_NEAREST = ON/OFF

If this option is turned ON, KAR will use the nearest base station to engage (Multi-baseline processing only).

KAR_MIN_ADD = NumMinutes

Minutes added to the minimum KAR time for every 10 km in baseline length. Default is 1.5 minutes.

KAR_MIN_TIME = L1time L2time

Minimum number of minutes for single and dual frequency processing before KAR is searching begins.

KAR_OUTPUT = ON/OFF

TRUE if KAR is to output additional information for FWD/REV files.

KAR_RELTOL = tol

Reliability is calculated by dividing the lowest intersection RMS by that of the second lowest. Reliable intersections should have values of 1.5 or higher and preferably greater than 2.0. Default is 1.5.

KAR_RMS_TOL = 0.075

Tolerance for KAR statistical test on the RMS phase. Default is 0.065 cycles.

KAR_RMSKEEPTOL = tol

If the RMS from a KAR solution is higher than this tolerance (cycles), then a warning will result. If there are still 4 good satellites (see KAR_MAXSV), this solution will not be used. Default value is 0.06 cycles.

KAR_RMSUSETOL = tol

This is the tolerance (cycles) with which intersections will be kept in the list. This value should be 0.20 or higher. The default is 0.20 cycles.

KAR_SEP_TOL = 2.0

Tolerance for allowable separation between the float and fixed KAR solutions. This option can be used to “kick out” solutions with large float/fixed separations.

KAR_STATIC = ON/OFF

Turn ON to engage KAR in static mode. By default this option is OFF.

KAR_STRICT_TOL = rmsflag relflag

rmsflag=ON/OFF and enables stricter RMS tolerance for rejecting bad KAR solutions. relflag=ON/OFF and it enables stricter reliability tolerance.

KAR_TWOSTAGE_SATS = 6

Use this maximum number of satellites in the KAR ambiguity search routines.

KAR_USE_DIST = ON/OFF MaxL1Dist MaxL2Dist

ON to prevent KAR from using long baseline data. Tolerances for single and dual frequency processing are in km. Normally computed automatically from KAR_DISTANCE.

KAR_USE_FAR = ON/OFF

ON if KAR to use all data less than distance tolerances. OFF will just use data until maximum distance exceeded. Default is off.

L2_LOCKTIME = ON/OFF

ON to use L2 locktime for cycle slip detection. For some receivers (for example, Ashtech), this can lead to more cycle slips being detected than really do occur.

L2_MAIN = ON/OFF

If turned ON, GrafNav will only use P2/L2 for single frequency processing (special applications only).

L2_SLIP_TOL = 0.20

Tolerance in L2 cycles at which an L2 cycle slip will be assumed. Default is 0.4 cycles.

LOCKTIME_CUTOFF = 8

Phase data will be ignored for the first 8 seconds after locking onto the satellite. Change this value to 0 to process all phase data or a large value to ignore the first n seconds of lock. This gives the phase lock loop a chance to stabilize.

MB_MASTER_ANT = L1VertHgt [L2Corr MeasDist SlantFlag(1/0) ProfileName] MeasToPC

This is the extended version of the antenna height for a multi-base master station. Only first two parameters and ProfileName used by processing engine.

MB_MASTER_DISABLE = ON/OFF

ON if the master station is to be disabled from processing.

MB_MASTER_FILE = Filename

The name of the multi-base master file (.GPB file). Use * as spaces.

MB_MASTER_INDEX = iIndex

Index of the master file in the project. Note that this starts at 0. It must proceed MB_MASTER_??? commands which refer to this location.

MB_MASTER_NAME = StaName

This is the name of the master station used in multi-baseline processing for identification and baseline settings matching. This name is also displayed on the map and used to refer to station/baseline specific settings.

MB_MASTER_POS = LatDeg LatMin LatSec LonDeg LonMin LonSec Ht(m)

These are the coordinates of a master station. The latitude and longitude must be entered in degrees minutes seconds with spaces in between. Latitude is positive in the Northern Hemisphere and negative in the southern. Longitude is positive in the Eastern Hemisphere and negative in the western (Americas).

MOVING_BASE = ON/OFF

Moving Baseline Option Only. If ON, this indicates that the base station is in dynamic mode as well as the remote. If MOVING_BASE=OFF, conventional processing is performed.

MOVING_BASE_FILE = Filename

No longer supported.

NAV_TOL = dist_in_m

Distance before using DGPS based navigation approximation. Affect Kalman filter convergence for slowly moving objects.

NOWRITE_HIGH = ON/OFF

Does not export epochs to the .FWD/.REV if statistics are too poor (if ON used).

OMIT = KAR/PROC \$name/ALL sv#/ALL RANGE/ALL [start end]

This controls omitted objects (such as baselines and satellites) from GrafNav processing. KAR = remove from KAR/fixed static; PROC = remove from all processing; \$name is baseline name (or use ALL); use start end to define RANGE of times to omit.

OUTPUT_MODE = NORMAL/EXTENDED

Determines output format for the ASCII FWD and REV files. EXTENDED includes velocity and ambiguity values.

POS_DENSITY = 1.0

This is the spectral density of the position states. The user may want to increase this value to 10 or more under high dynamics. This value should be left at 1.0 (default).

PPP_SP3_DATUM = Datum Conversion

Datum used for SP3 precise ephemeris and associated conversion to local datum.

PPP_PROCDISC = Description

Description of processing run. Used by *Processing History* feature.

PPP_PROCTIME = Time Date

Time, in *HH:MM:SS* format, and date, in *MM/DD/YY* format.

PPP_PROCUSER = Name

Name or initials of user. Used by *Processing History* feature.

PPP_PROCESS_MODE = PPP/SFCA/DFCA/AUTP

Specifies the single point processing mode. Dual frequency carrier phase [PPP], single frequency C/A code (SFCA), dual frequency C/A code (DFCA), automatic (AUTO).

PPP_USEP1OVERCA = ON/OFF

Turn ON to use P1 measurements in place of C/A code measurements. Requires new GPB format.

PPP_USESOLVEDCLOCK = ON/OFF

ON to use solved clock bias, or OFF to use corrected receive time from GPB file.

PPP_PRECISEONLY = ON/OFF

ON if only satellites with precise ephemeris and clock values are to be used.

PPP_PROCESS_DIR = FORWARD/REVERSE SINGLE/BOTH

First value indicates processing direction, while second is used by the interface to implement both directions.

PPP_SLIP_TOL = dCoarse dFine

Coarse and fine cycle slip tolerances, in cycles.

PPP_LOCKTIME = ON/OFF ON/OFF

Determines whether or not to use L1 and/or L2 locktime counters.

PPP_USE_DOPPLER = ON/OFF

ON if Doppler observable is to be used during processing.

PPP_DYN_MODE = LOW/MEDIUM/HIGH

If Doppler not used, this command determines level of dynamics modeling.

PPP_OUTPUT = NORMAL/EXTENDED ON/OFF

Determines whether to use standard or extended (with covariance information) output, and whether or not to include bad data.

PPP_TROPO = ON/OFF dDensity

Turns on/off tropospheric error state. If ON, specify the spectral density.

PPP_STD_MODE = Mode

Automatic [AUTO], elevation-based [ELEV], C/N0-based [CN0], or STANDARD.

PPP_STD_REJECT = Type CedeRej PhaseRej DopRej CedeReset PhaseReset

TYPE=MANUAL/NORMAL/STRICTALL/STRICTPHASE/STRICT-CODE/LOOSEALL/LOOSECODE/LOOSEPHASE, values are nSD that is, number of standard deviations. If type is MANUAL, the user needs to enter the rejection and reset tolerances.

PPP_STD_SKIP = MaxRejSec nSkipCodeEpochs nSkipPhaseEpochs

These are the advanced reset settings.

PPP_STD_RELTOL = Value

This is the reliability tolerance for rejecting outliers.

PPP_ETCOFF = ON/OFF

Enables or disables Earth tide corrections.

PPP_PWOFF = ON/OFF

Turns on/off phase wind-up correction.

PPP_NOECLIPSE = ON/OFF

OFF to account for satellite eclipse.

PPP_EPHRELCORR = ON/OFF

ON to use the relativity correction derived from the SV ephemeris instead of from the SP3.

PPP_SEPARATECLKS = ON/OFF

Enables or disables the use of separate clock states for the phase and code. Should be ON for Trimble users.

PPP_CODEONLY = ON/OFF

ON to for code-only processing.

PPP_NODCB = ON/OFF

ON to apply DCB correction for C/A – P1 bias.

PROCESSDESC = Description

This is the processing description. By default it uses Run(1) and increments after each processing run. The information is stored in the processing history. Use * for spaces.

PROCTIME = Time Date

Time (hh:mm:ss) and date (mm/dd/yy) of processing.

PROCUSER = Name

User's name or initials stored before processing. It is stored in the processing history (by GrafNav) and is outputted in ASCII and binary files.

PROCESS_DIR = direction

Processing direction is either FORWARD or REVERSE. Reverse processing can be useful if there are a major series of (fatal) cycle slips during a kinematic run. All features supported under forward processing are supported under reverse processing.

REMOTE_ANT = L1AntHgt [L2Offset ...

Vertical offset from ground location to L1 phase centre. Second value is offset from L1 to L2 phase centre. Additional values used by GrafNav for internal use (see MB_MASTER_ANT).

REMOTE_FILE = [path]file_prefix[.gpb]

This is the name and location of the remote station binary GPS data file. This data must be in the .GPB format. If the data is not in this format, use one of the conversion utilities supplied. If this value is not entered, the program will prompt for it. Make sure to replace all spaces with '*' characters.

REMOTE_POS = lat long ht

These are the coordinates of the remote station. The latitude and longitude must be entered in degrees minutes seconds with spaces between. The processing engine now computes a differential pseudo-range solution at the start of the program if REMOTE_SD is greater than 1.0 meters. This means that this position can be many kilometers out and still work. Entering the position is not necessary. Latitude is positive in the Northern Hemisphere and negative in the Southern. Longitude is positive in the Eastern Hemisphere and negative in the Western Hemisphere (for example, Americas). See also INITEX command.

RMS_MODE = NEW/OLD

No longer supported.

SAVE_AMB = ON/OFF

ON if ambiguities are to be saved if a satellite drops out in the file but it's locktime is not reset. Disable if too many filter resets are occurring because of missed cycle slips.

SF_IONO_MODE = OFF/ON/BROADCAST/IONEX

Turned ON for automatic selection between IONEX and ICD-200 broadcast ephemeris corrections to be applied when processing single frequency data, or select type of correction manually. Such corrections will only help on very long baselines.

SHOTGUN = ON/OFF

No longer supported.

SKIP_NOREPAIR = CaVal L1Val

Maximum number of seconds of skip if bad data observed and could not be corrected on either L1 or C/A. Defaults are 10 s for C/A and 0.0 s for L1. Values are in seconds.

SPLIT_SS = ON/OFF dt

Set ON to break up static sessions if a time gap of greater than dt is observed. Dt is in seconds. By default, this setting is OFF.

SP_???

Single point processing settings. Ignored by NGPS32.dll.

STANAME = name

Used by GrafNet to set the station name for display in output files.

STATIC_SLIP_TOL = val

Static cycle slips are declared if greater than val, which is in cycles.

STATICSESS = ID AntHgt StartTime EndTime IsSec80 UseFix 0

Define information about a static session. For instance, ID gives it's name (use '*' for spaces); AntHgt allows the antenna height to be changed (value in m); Start/EndTime define time range in TOW or seconds since 1980 (see IsSec80 flag); IsSec80=on/off; UseFix indicates whether fixed static solution is to be used (0=off, 1=use, 2=check distance and time, see FIX_AUTO command)

STD_MODE = AUTO/ELEV/CN0/STANDARD

This is the type of weighting mode that the measurements will use in terms of statistical handling.

STD_REF = REFCN0 REFELEV CN0_V

These are the reference values that the measurement standard deviation's refer to. V in SD = $V+10\text{-cno}/10$ (note: scaled by REF_CN0)

STD_DIST = LOW/MEDIUM/HIGH/OFF/MANUAL [ManHzPPM ManVPPM]

This is the magnitude of distance dependent errors. The distance effect can be low, medium, high, or off. The user can override these settings and enter their own horizontal and vertical PPM manually.

STD_PPM = RejectPPM

This is only used if the user command STD_DIST = OFF above.

STD_REJECT = Type CedeRej PhaseRej DopRej CedeReset PhaseReset

TYPE=MANUAL/NORMAL/STRICTALL/STRICTPHASE/STRICT-CODE/LOOSEALL/LOOSECODE/LOOSEPHASE, values are nSD that is, number of standard deviations. If type is MANUAL, the user needs to enter the rejection and reset tolerances.

STD_SKIP = MaxRejSec nSkipCodeEpochs nSkipPhaseEpochs

These are the advanced reset settings.

STD_PHASE = SD_m ON/OFF

This is the standard deviation for the carrier phase. ON/OFF refers to if the standard deviation will be adjusted for additional ionospheric noise.

STD_CODE = SD_m

This is the standard deviation for the C/A code and P code.

STD_DOPPLER = SD_m/s ON/OFF

This is the standard deviation for the Doppler. ON/OFF refers to the auto-doppler flag (used in GrafNav only).

STD_BL = Name UseMain(ON/OFF) [CodeSD phaseSD dopplerSD]

These are baseline specific values. Name refers to master; values in m or m/s.

STD_RELTOL = Value

This is the reliability tolerance for rejecting outliers.

STD_PHASE = SD_m ON/OFF

This is the standard deviation for the carrier phase. ON/OFF refers to if the standard deviation will be adjusted for additional ionospheric noise.

STD_CODE = SD_m

This is the standard deviation for the C/A code and P code.

STD_DOPPLER = SD_m/s ON/OFF

This is the standard deviation for the Doppler. ON/OFF refers to the auto-Doppler flag (used in GrafNav only).

TIME_CORR = 0.0 0.0

seconds. Time correction to master and remote files. This may be useful if a receiver has logged data in UTC time rather than GPS time. It is not suggested that this command be used unless there are errors in the GPS data timing.

TIMERANGE = ALL/RANGE StartSec EndSec Flag ShowHmsMdy

Processing time range. Replaces START_TIME and END_TIME commands. ALL processes entire data set. StartSec is time at beginning (regardless of forward or reverse processing). EndSec is time at end of processing period. Times can either be seconds of the GPS week or seconds since 1980 (see Flag). Flag is 0 for time not valid, 1 for seconds of the week, and 2 for seconds since 1980. ShowHmsMdy is only used by GrafNav for display purposes (1=show H:M:S ...).

TROPO_MODEL = OFF/SAAS

Default is SAAS, which is the Saastamoinen model. OFF can be used with GPS simulators that have tropospheric correction disabled.

USE_DOPPLER = ForCarrier ForCode

ForCarrier uses Doppler for carrier phase (ON/OFF); ForCode uses Doppler for code only processing (ON/OFF).

USE_PCODE = P1forCA(ON/OFF) P2(ON/OFF)

This will enable P-code and requires dual frequency processing.

USERKAR = gpstime FORWARD/REVERSE/BOTH

Engage KAR at this time for the direction(s) specified, may be multiple entries. gpstime is in seconds of the GPS week.

VEL_DENSITY = density

Spectral density for velocity states (m2/s2).

VERBOSE = ON/OFF

ON prints additional information to FWD/REV/FML/RML files.

VERSION = #.#.#

Ignored by .dll. It is used by GrafNav to indicate version number producing CFG file.

WRITE_BAD_EPOCHS = OFF/ON

Default is OFF. Use ON to write bad data to the .FWD/.REV files. This option is useful if the user wishes to view data at epochs where the RMS_TOL values are exceeded. Normally, data which is greater than RMS_TOL is not written to file.

WRITE_RESIDUALS = ON/OFF

Default is OFF. If ON, then write out each L1 phase and CA-code residual for each satellite to a .RL1 and .RCA file.

WRITE_SLIP_MSG = ON/OFF

ON if cycle slip and other satellite rising/falling warning messages to be written to message log.

Baseline

Connection between two stations with one or more sessions. Normally, a session and a baseline can be considered the same. However, in some cases there may be more than one session per baseline. This is called a duplicate session baseline, and it is plotted yellow on the screen.

Check Point

A station with known coordinates, but these coordinates are only used as a check against GrafNet's computed coordinates.

Control Point

See **Station** or **GCP**.

Ground Control Point (GCP)

A reference station with known latitude, longitude and height coordinates. The user may also assign horizontal and vertical standard deviations for these values. There can be horizontal, vertical or 3-D points, and there must always be at least one 3-D point or else one horizontal and one vertical point per project.

Observation

A raw measurement file collected from a receiver set up over a stationary point. GrafNet only accepts GPB files and, thus, other formats must be converted first. See *Table 2, Supported Data Formats for Post-Processing* on page 15 for supported formats. GrafNet also requires single frequency carrier phase data as a minimum, and accepts dual frequency if available. Users wishing to perform code-only processing should use GrafNav.

Session

Concurrent period of time between two observation files at two different stations. One of the two stations will be the remote, and the other will be the master. The arrow on the screen will be pointing from the master to the remote. The direction is determined by GrafNet in order to form loop closures as well as to minimize the number of legs from a control point. Each session will be processed individually and combined in either a network adjustment or traverse solution. A session can have different statuses and colors depending on whether certain tests passed or failed.

Station

A point where the GPS receiver was setup over and there might be multiple observation files for a single station. However, one set of position values will be produced for each station as a final product of GrafNet. There are several types of stations.

Tie Point

Such a point may also be called a *loop tie closure* and is formed when two or more sessions point to it. Thus, there is a redundant determination at this point.

Traverse Station

This is a point with no tie or control information. It might have two stations connected to it, but one is pointing to it and the other is pointing from it.

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