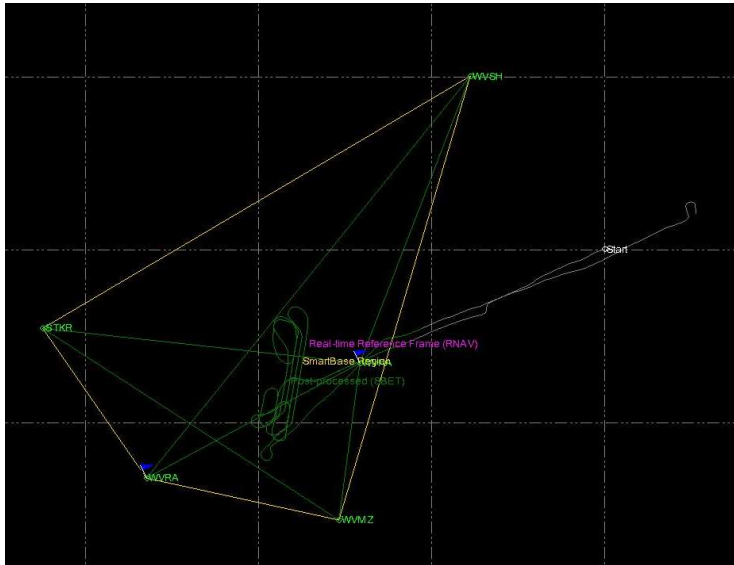


Appendix A: 2019 GPS and IMU Processing Reports for Each Mission

45A19078A



Project Settings

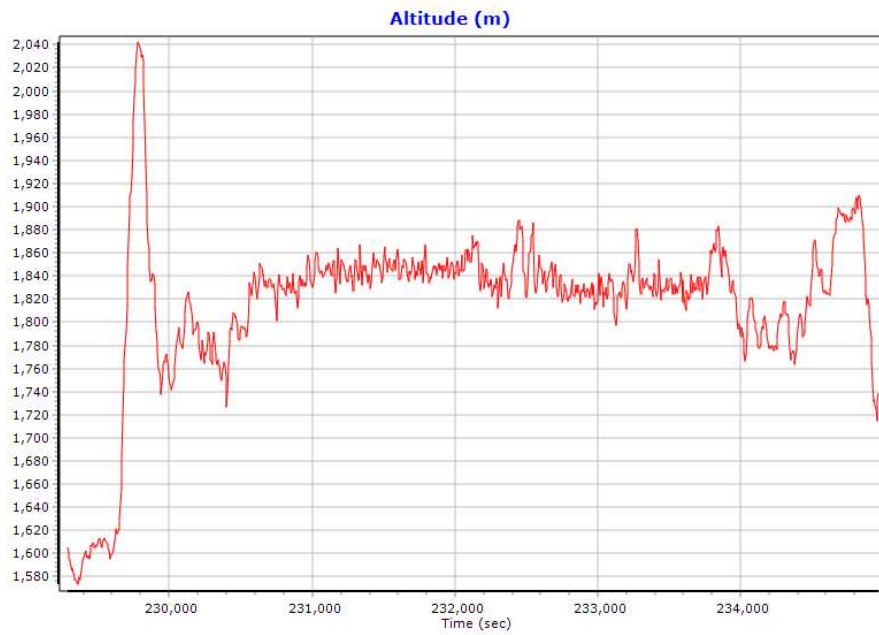
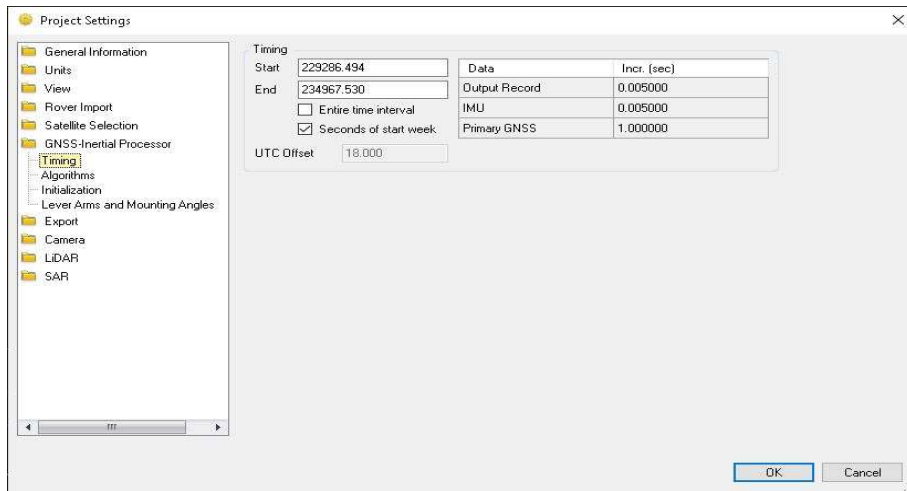
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LIDAR
- SAR

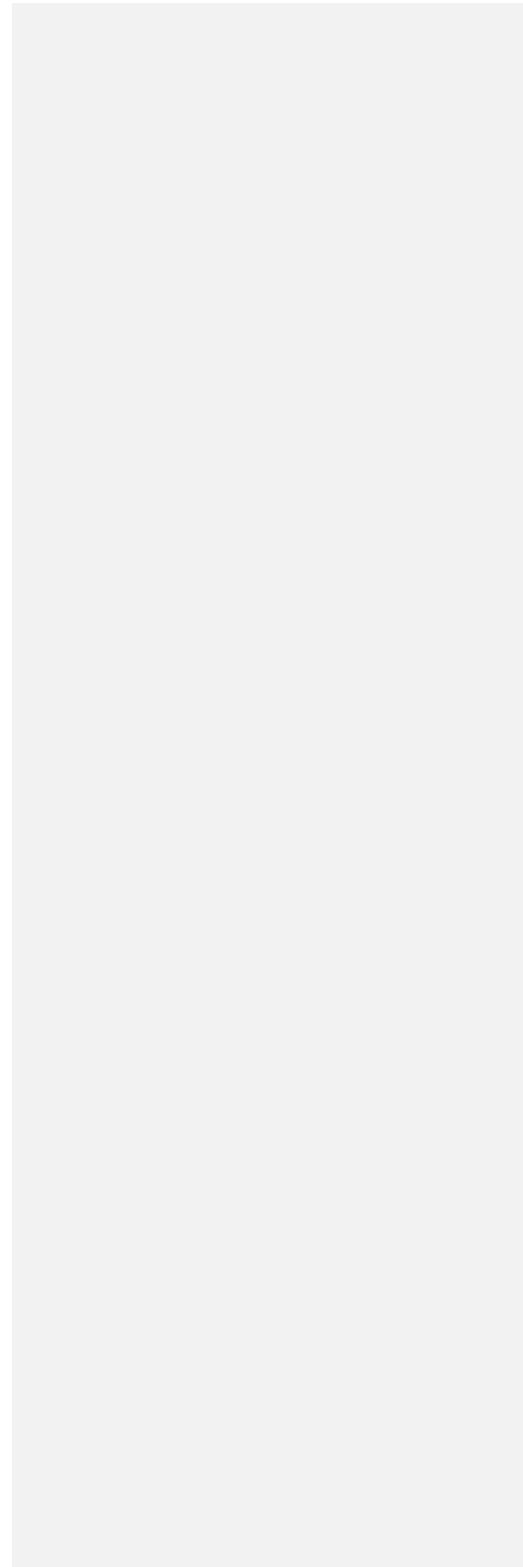
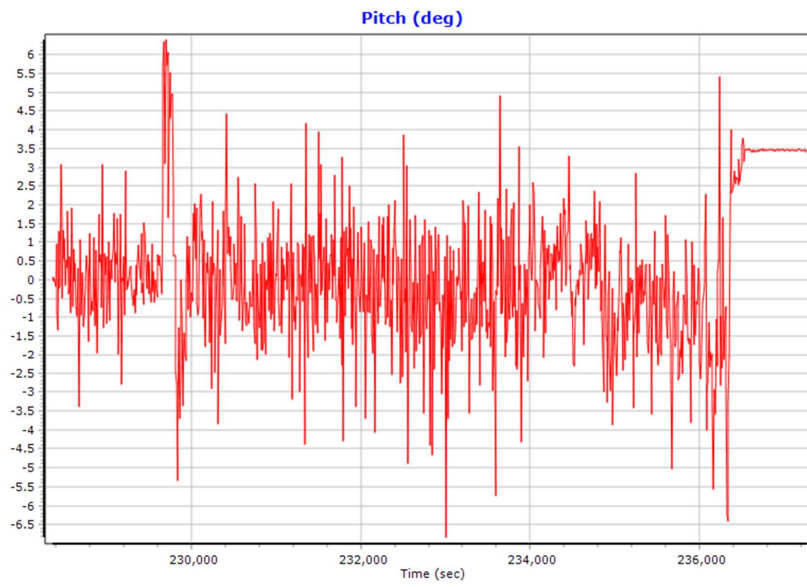
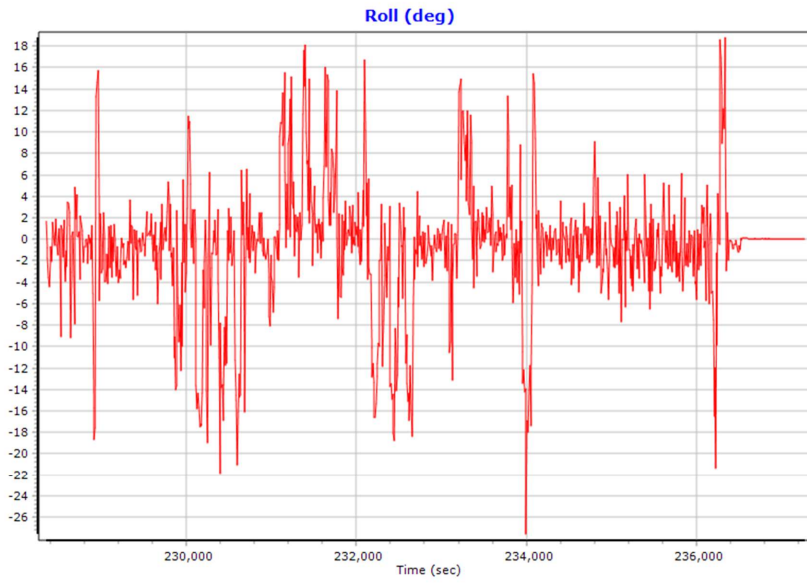
| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
|----------------------------|----------------------------------|
| X: 0.034 m | X: 0.000 deg |
| Y: -0.010 m | Y: 0.000 deg |
| Z: -0.352 m | Z: 0.000 deg |

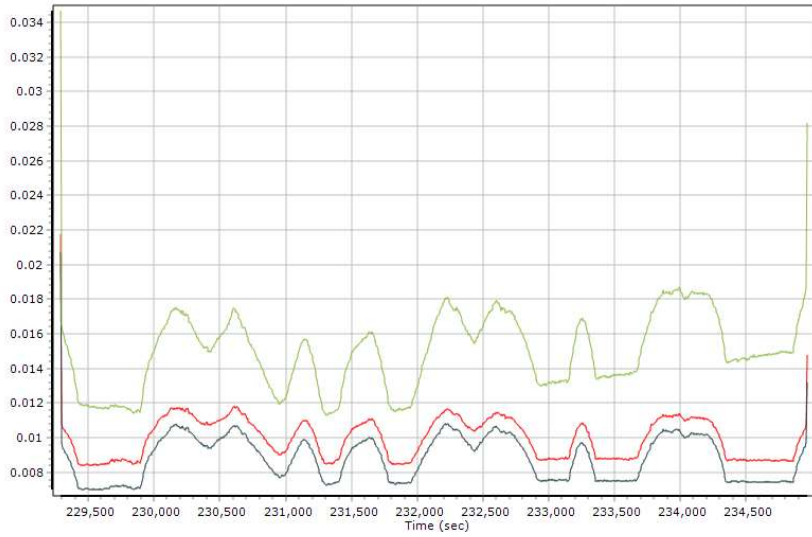
| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
|-------------------------------------|---------------------------------------|
| X: -0.049 m | X: 0.000 deg |
| Y: 0.003 m | Y: 0.000 deg |
| Z: -1.230 m | Z: 0.000 deg |

Standard Deviation: <3cm 10cm 50cm 1m 10m

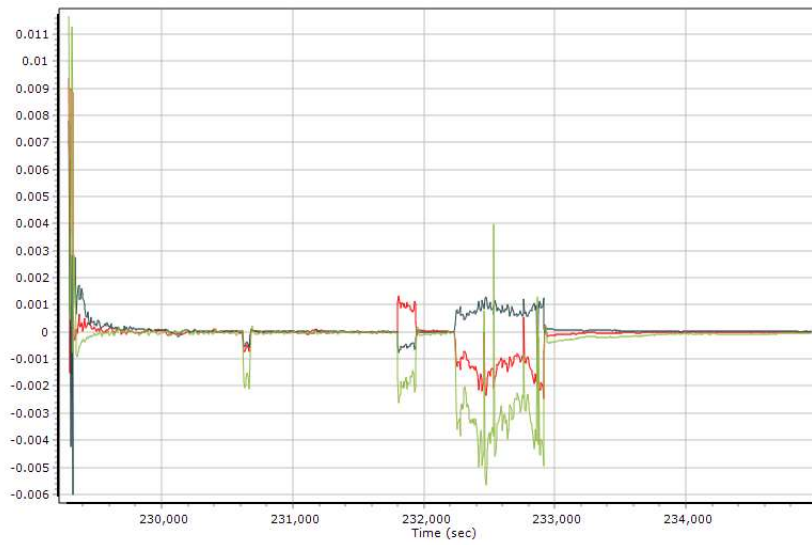
OK Cancel



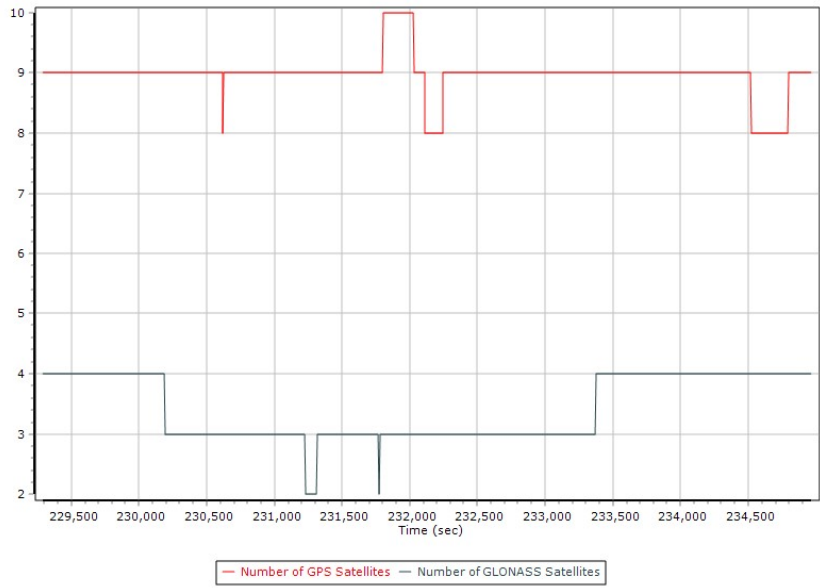




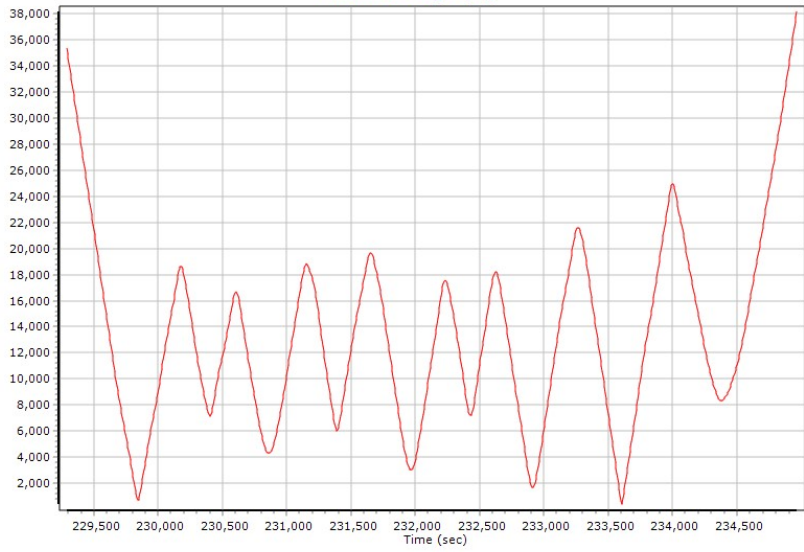
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)

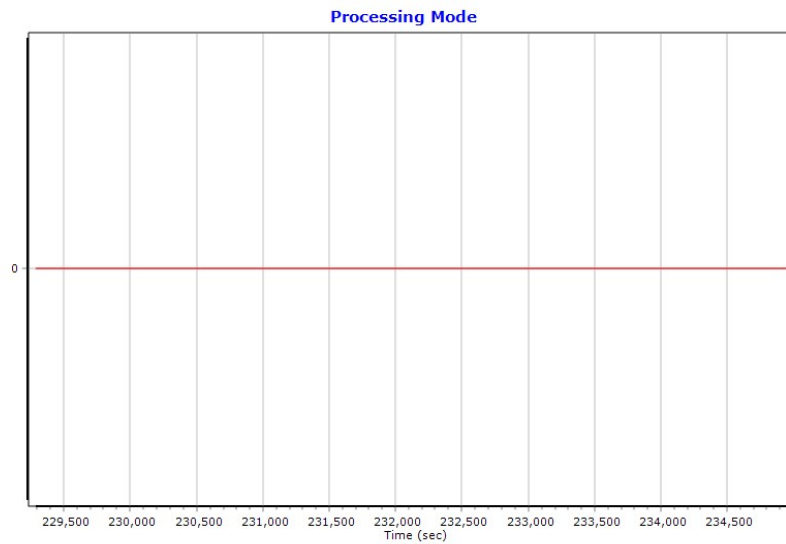
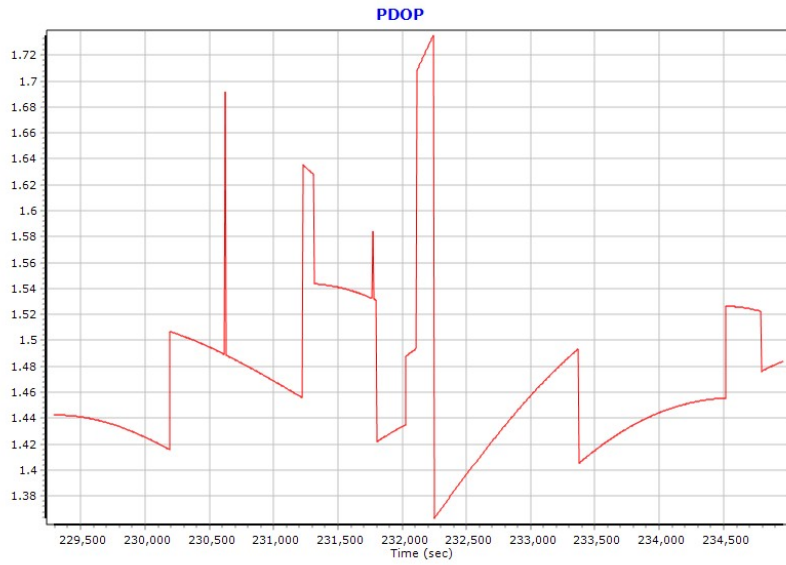


— North (m) — East (m) — Down (m) — DR mode

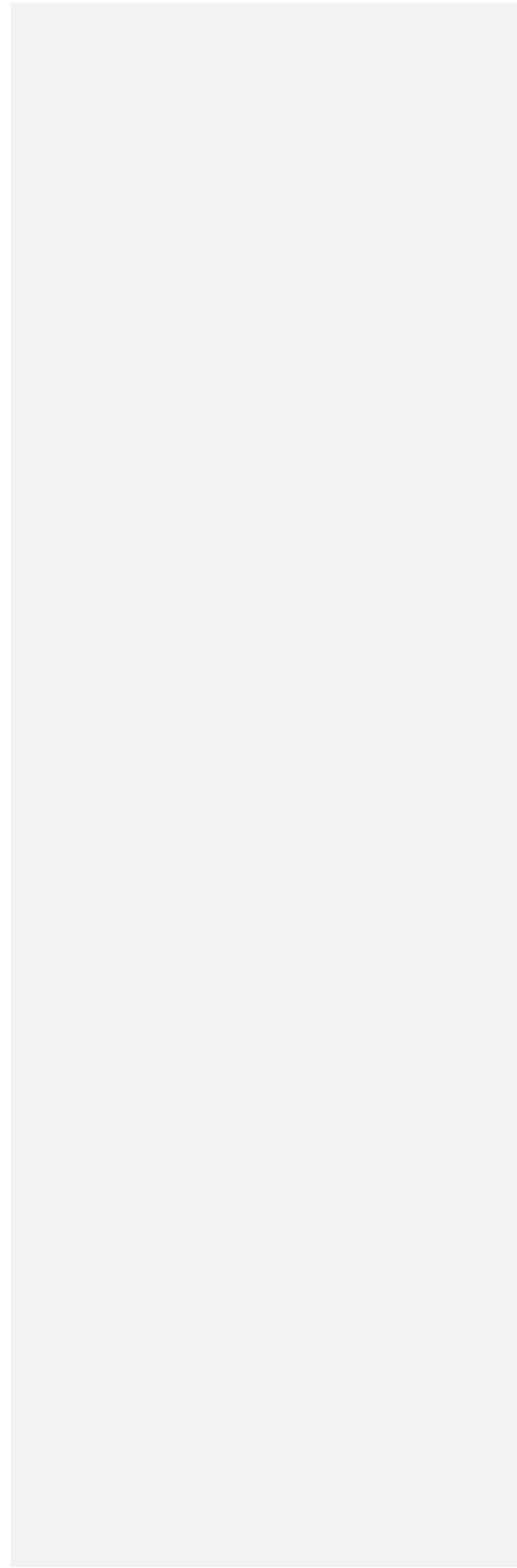


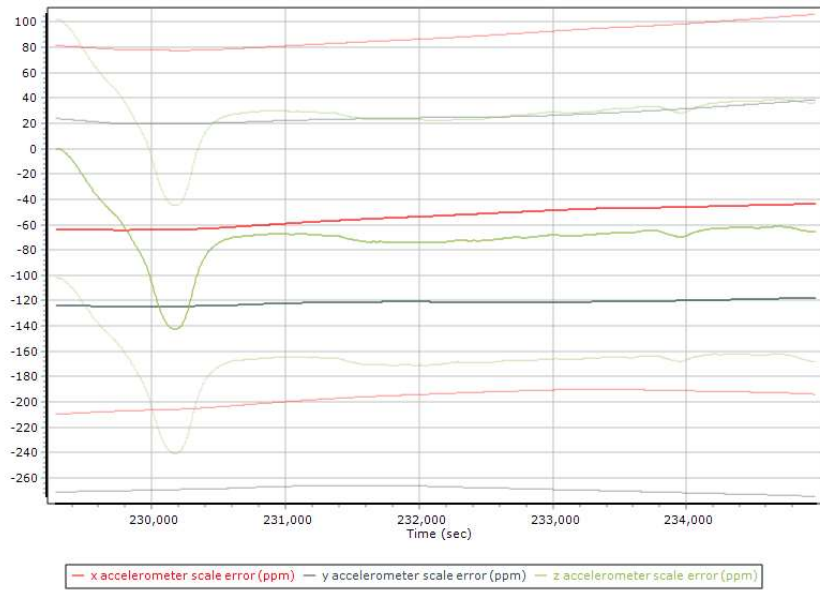
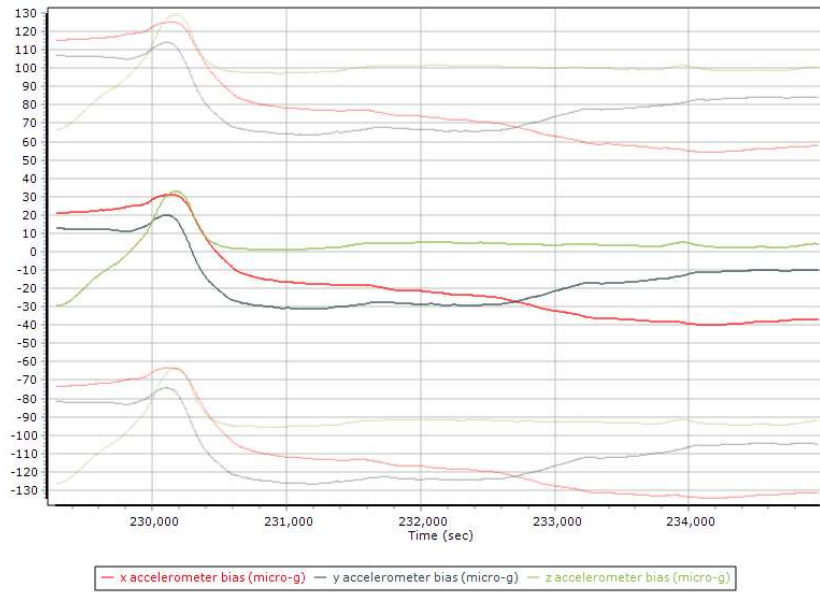
Baseline Length(m)

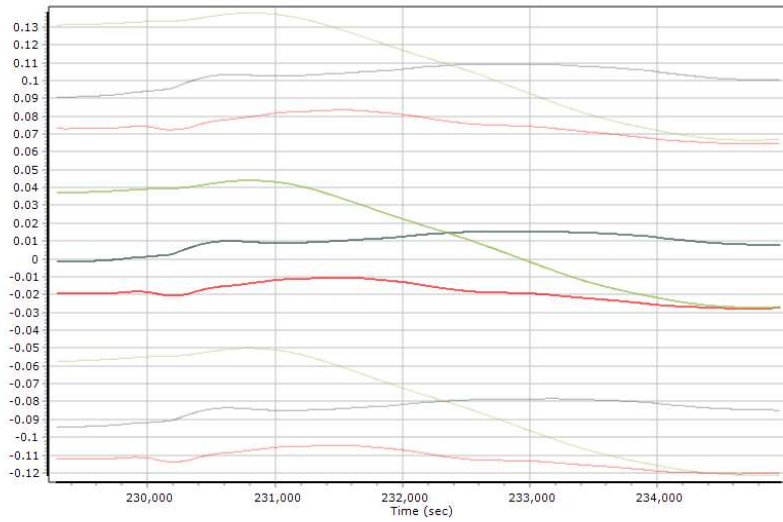




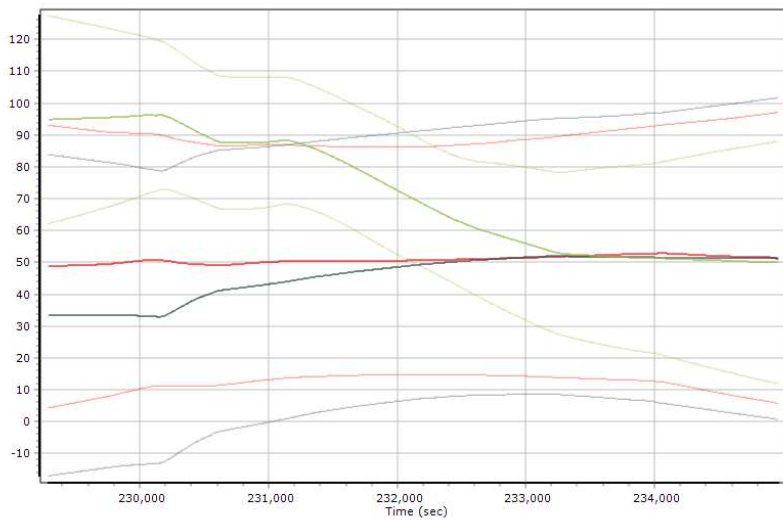
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR





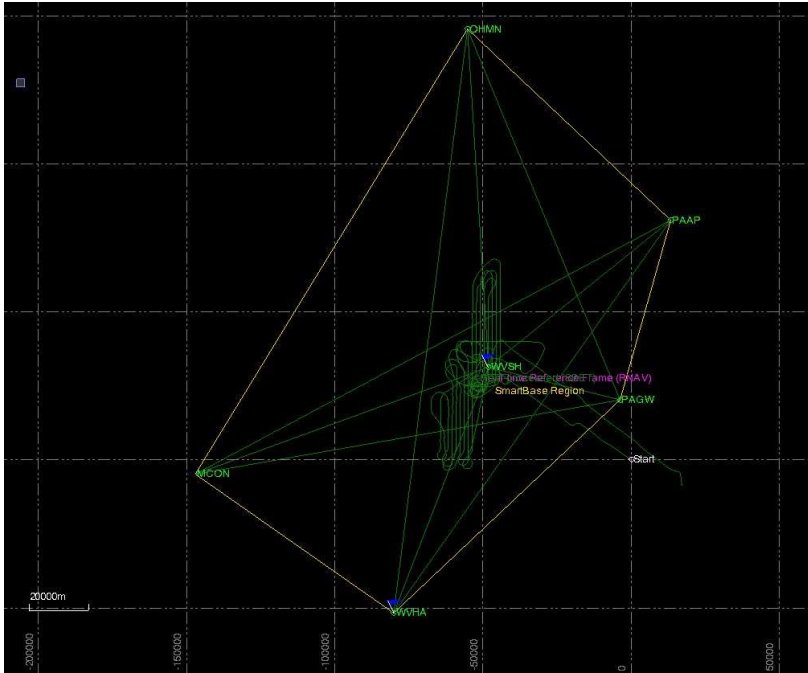


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



— x gyro scale error (ppm) — y gyro scale error (ppm) — z gyro scale error (ppm)

45A19079A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LIDAR
- SAR

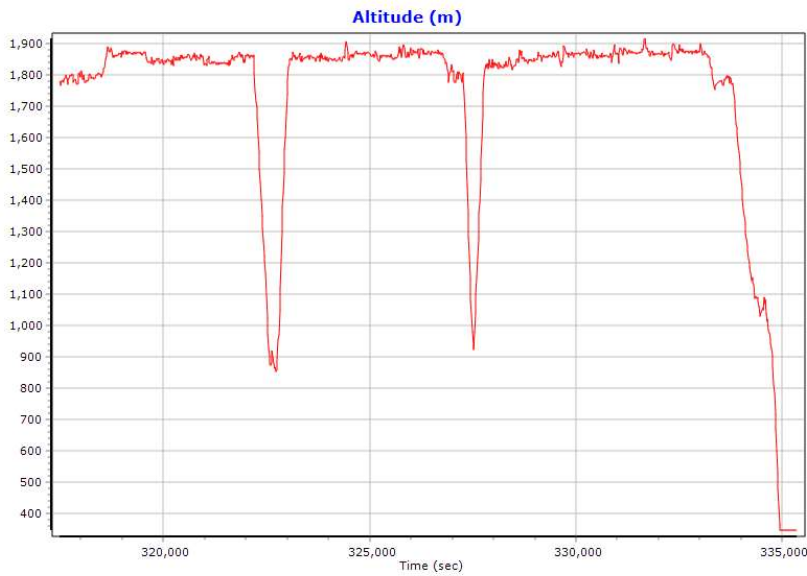
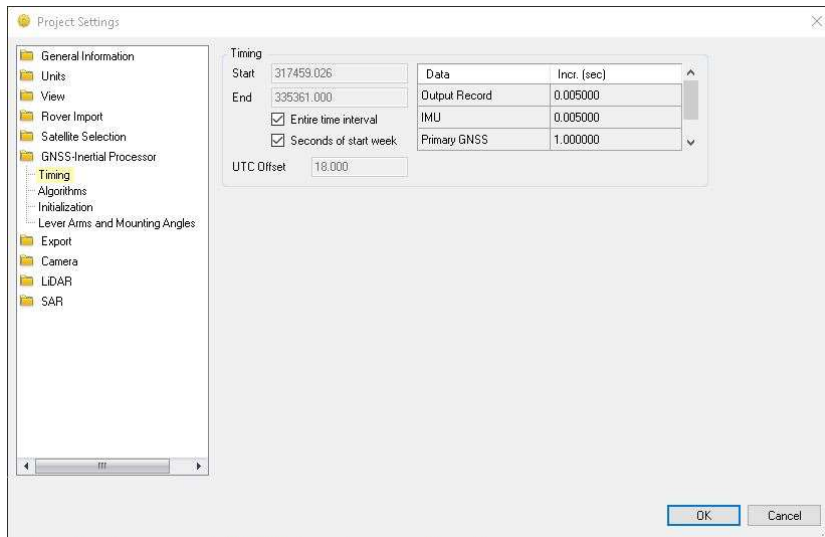
| Stabilized Mount to IMU Lever Arm | | Stabilized Mount to IMU Mounting Angles | |
|-----------------------------------|----------|-----------------------------------------|-----------|
| X | -0.034 m | X | 0.000 deg |
| Y | -0.010 m | Y | 0.000 deg |
| Z | -0.352 m | Z | 0.000 deg |

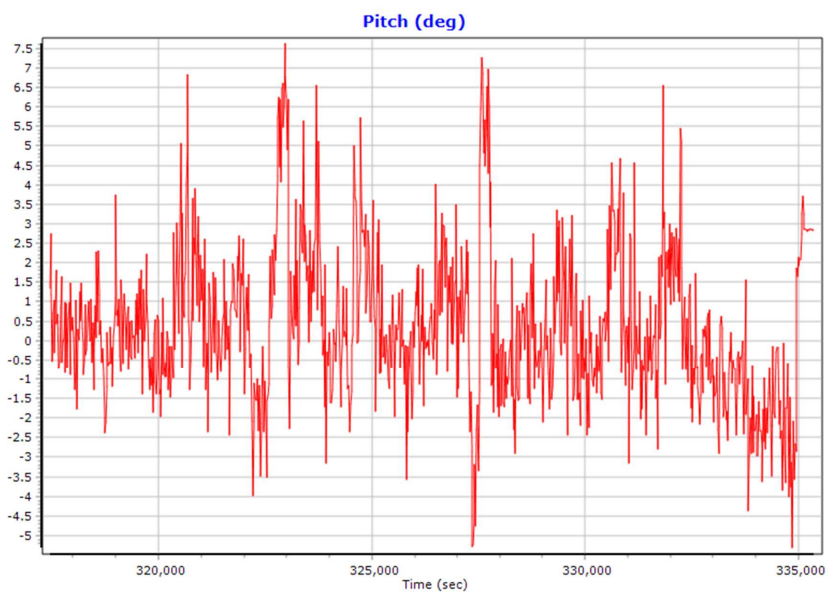
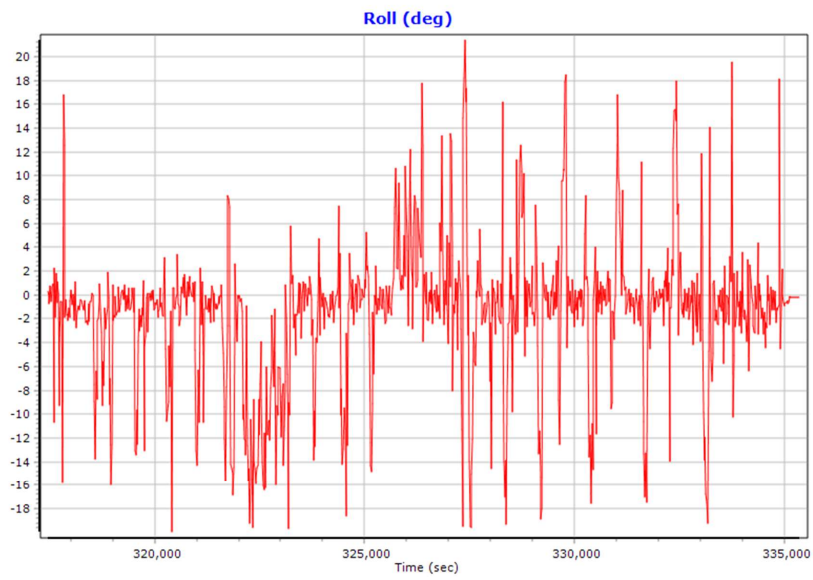
| Stabilized Mount to Primary GNSS Lever Arm | | Aircraft to Stabilized Mount Mounting Angles | |
|--------------------------------------------|----------|----------------------------------------------|-----------|
| X | -0.049 m | X | 0.000 deg |
| Y | 0.003 m | Y | 0.000 deg |
| Z | -1.230 m | Z | 0.000 deg |

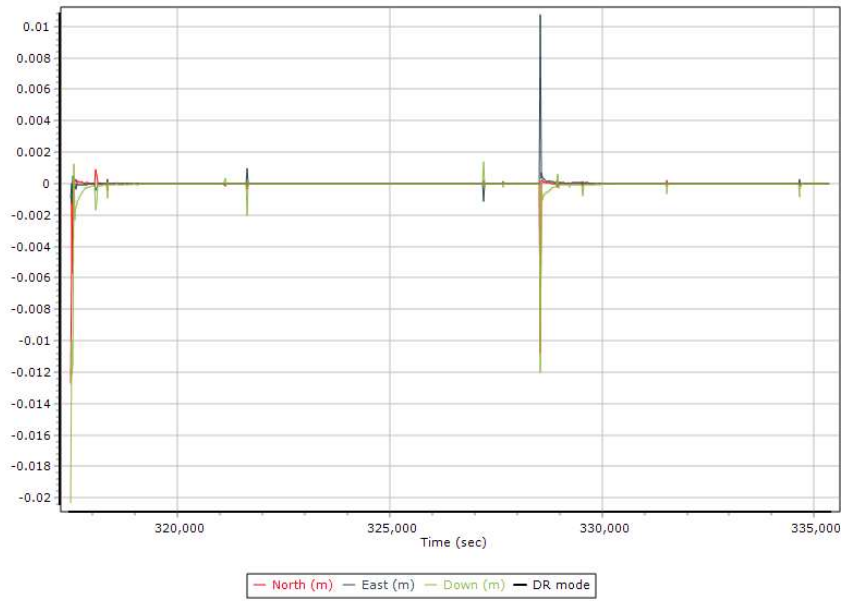
Standard Deviation: <3cm 10cm 50cm 1m 10m

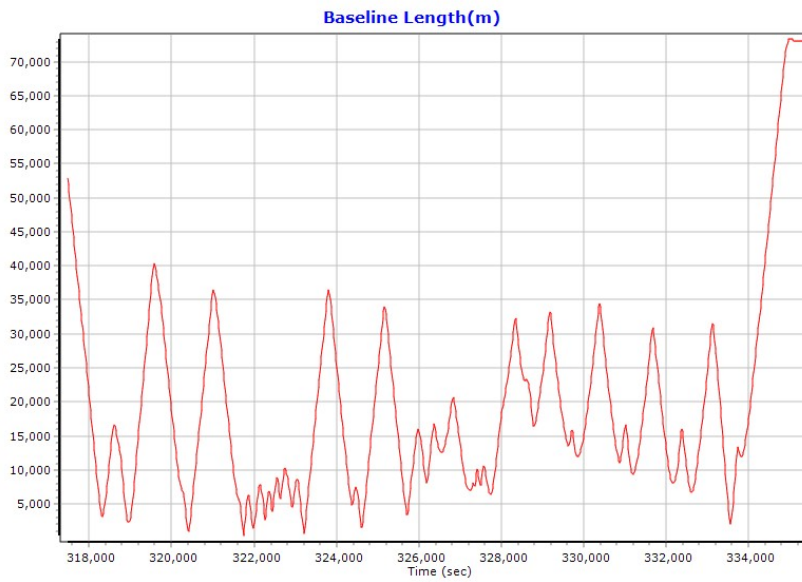
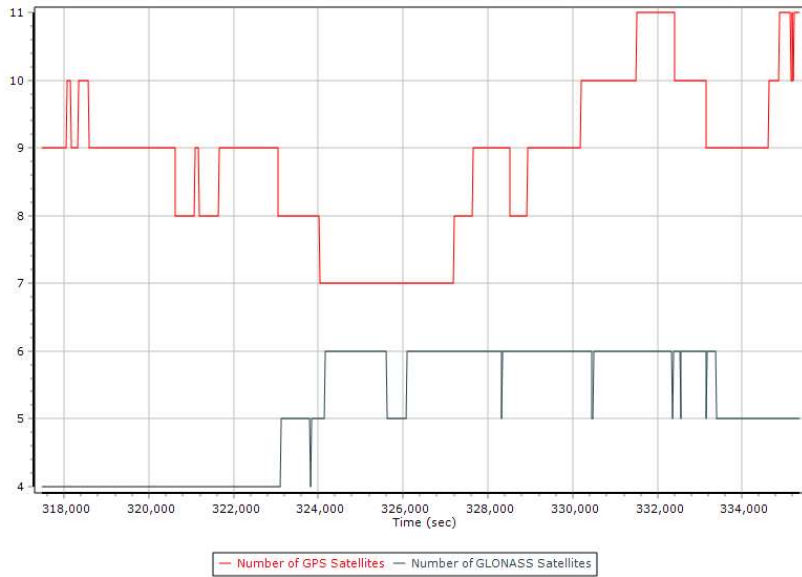
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

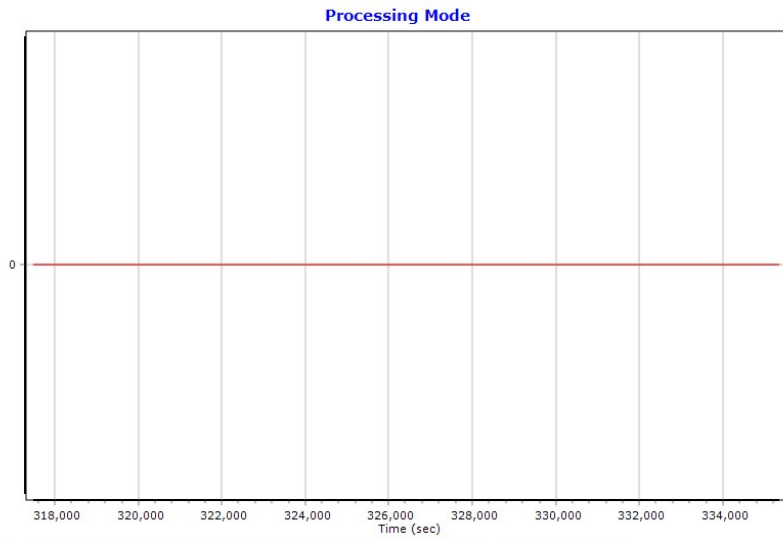
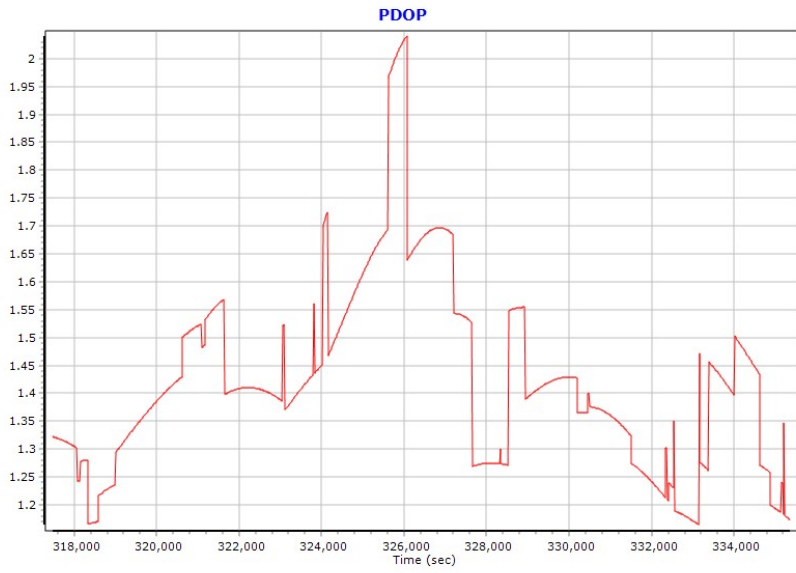
OK Cancel



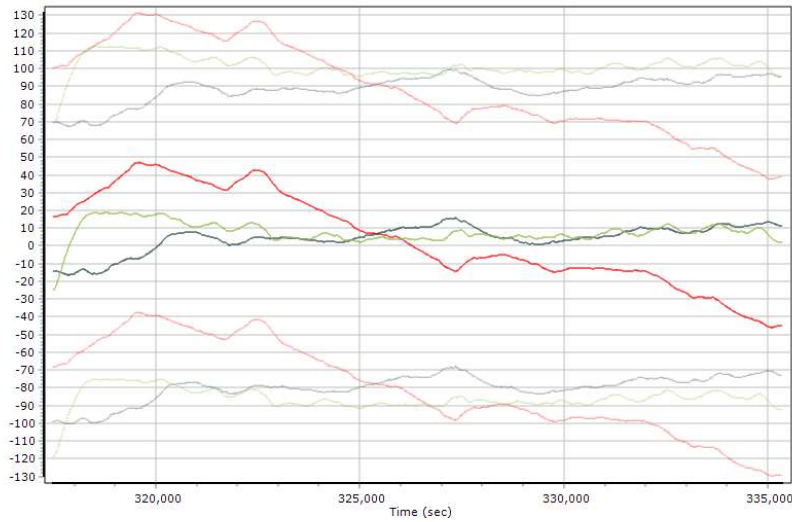




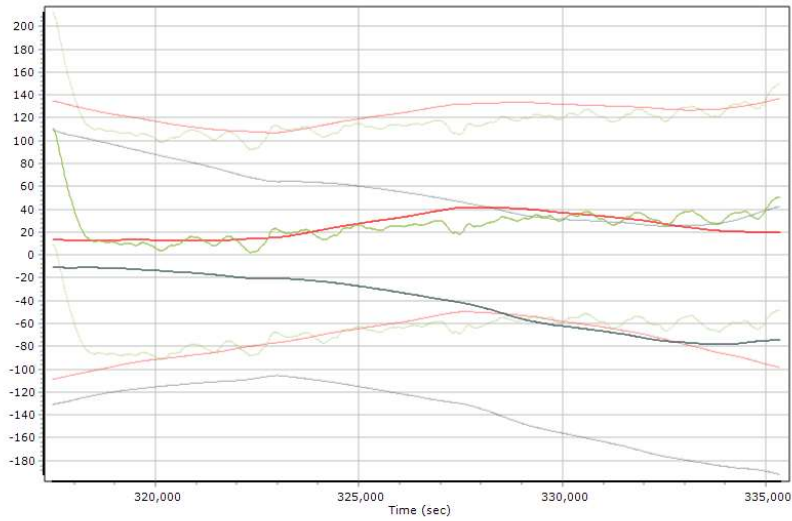




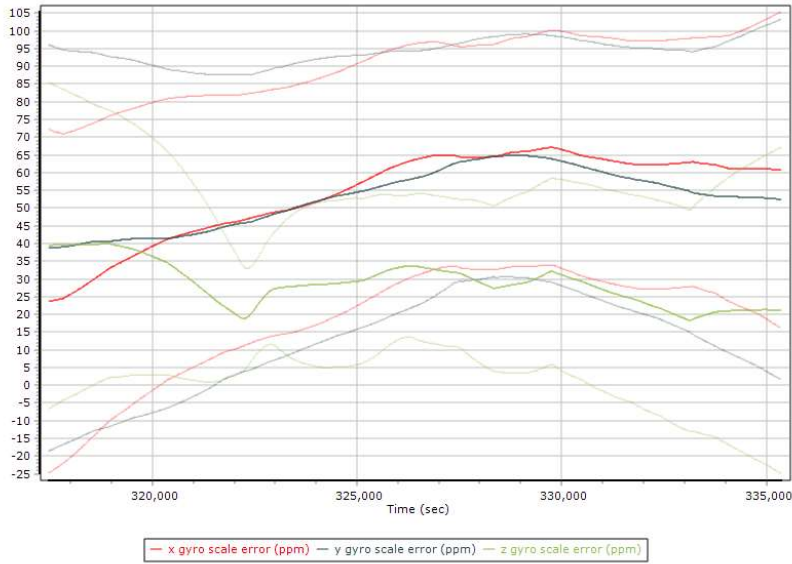
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



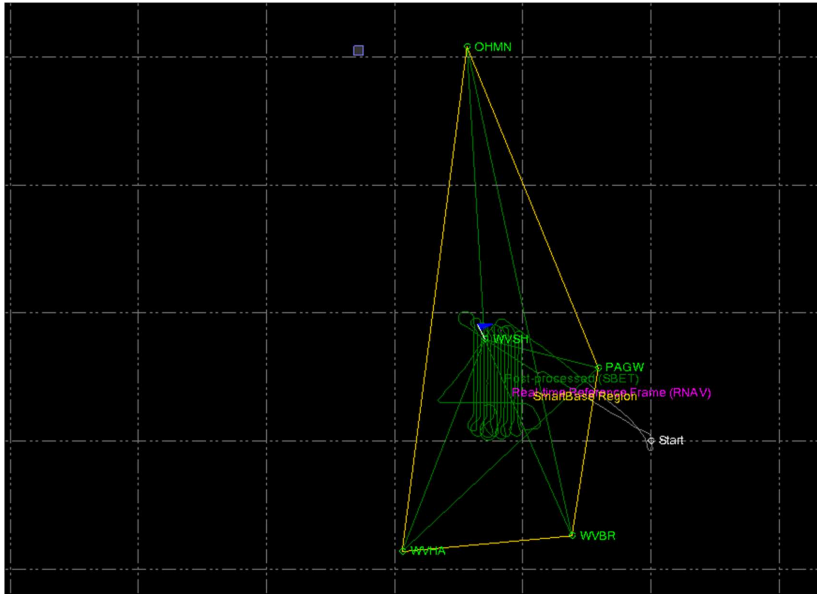
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)



x accelerometer scale error (ppm) y accelerometer scale error (ppm) z accelerometer scale error (ppm)



45A19082A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

Stabilized Mount to IMU Lever Arm

| | |
|---|---------------------------------------|
| X | <input type="text" value="-0.034 m"/> |
| Y | <input type="text" value="-0.010 m"/> |
| Z | <input type="text" value="-0.352 m"/> |

Stabilized Mount to IMU Mounting Angles

| | |
|---|----------------------------------------|
| X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="0.000 deg"/> |

Stabilized Mount to Primary GNSS Lever Arm

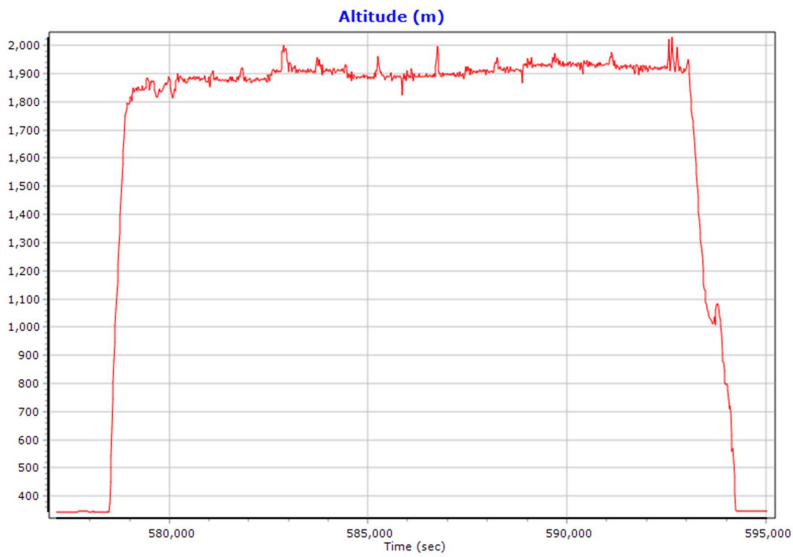
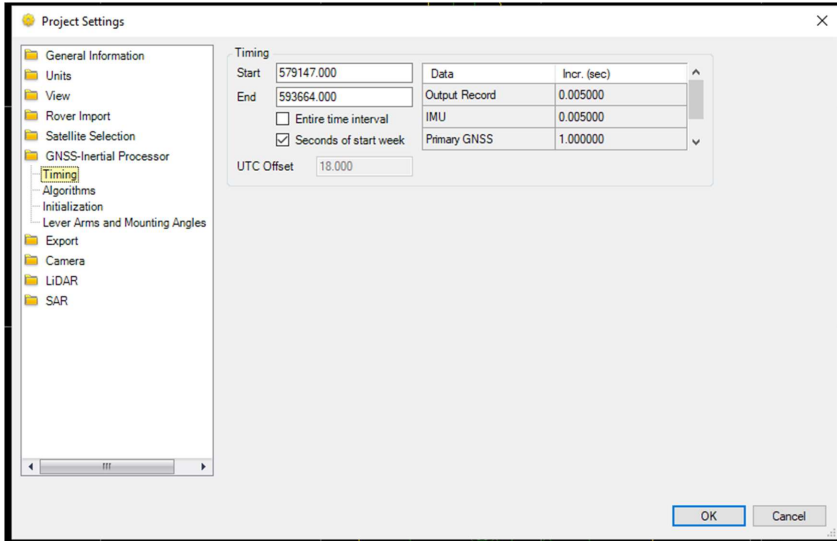
| | |
|---|---------------------------------------|
| X | <input type="text" value="-0.049 m"/> |
| Y | <input type="text" value="0.003 m"/> |
| Z | <input type="text" value="-1.230 m"/> |

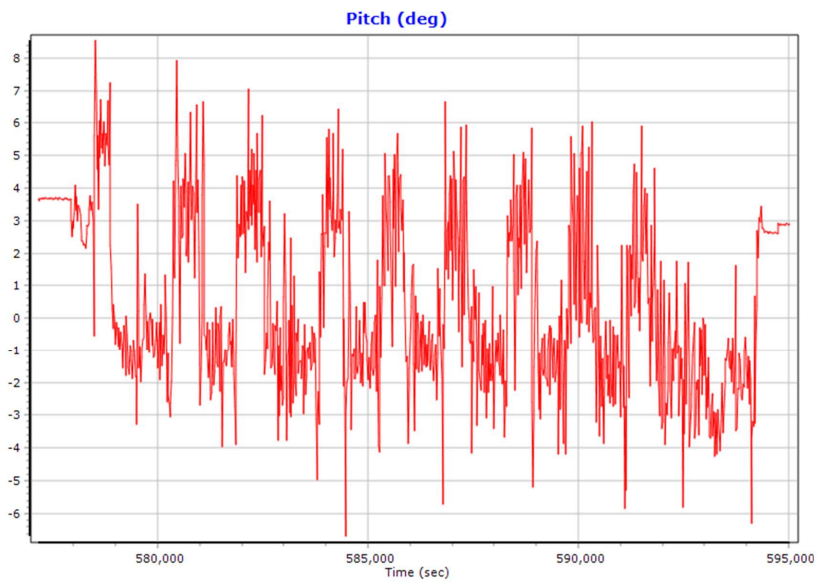
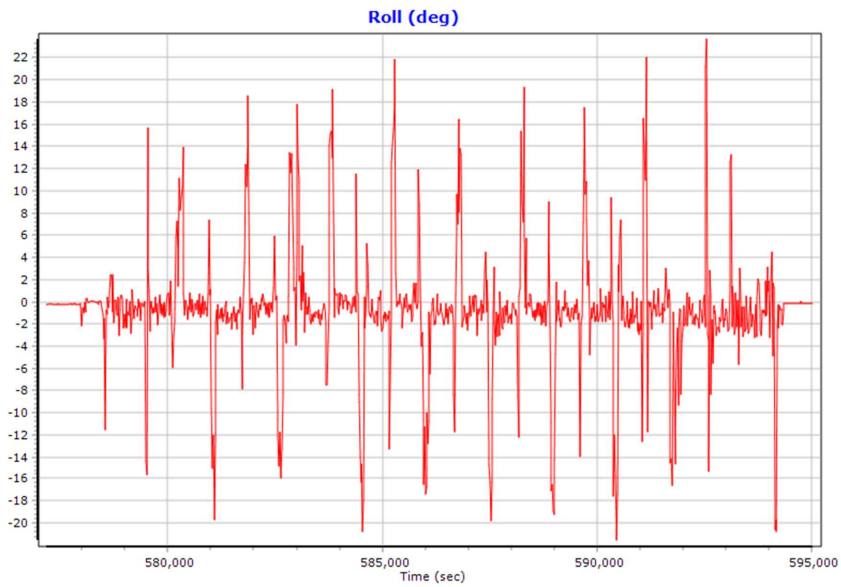
Aircraft to Stabilized Mount Mounting Angles

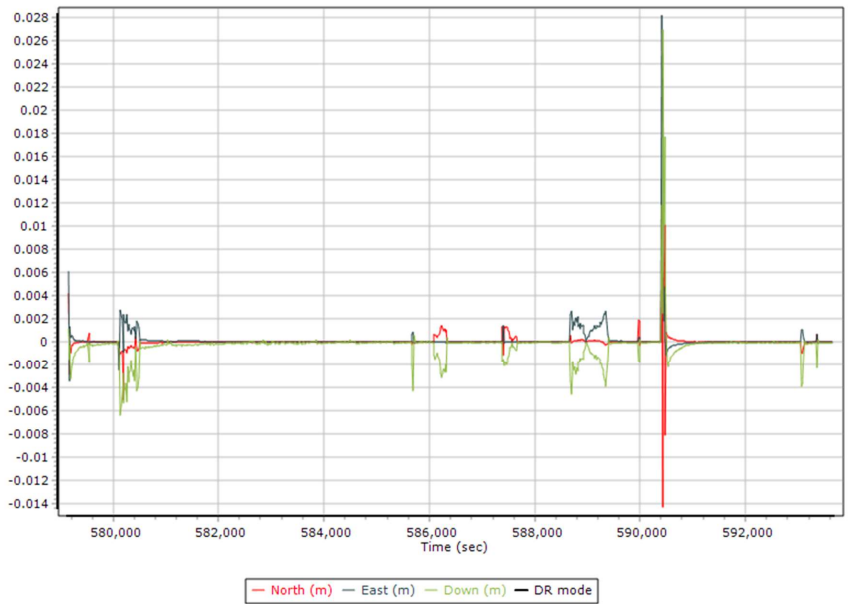
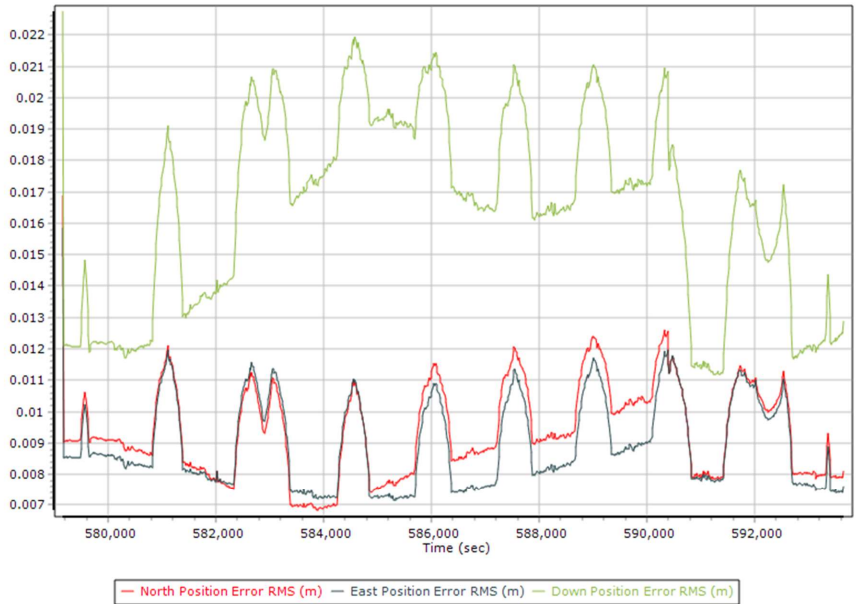
| | |
|---|----------------------------------------|
| X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="0.000 deg"/> |

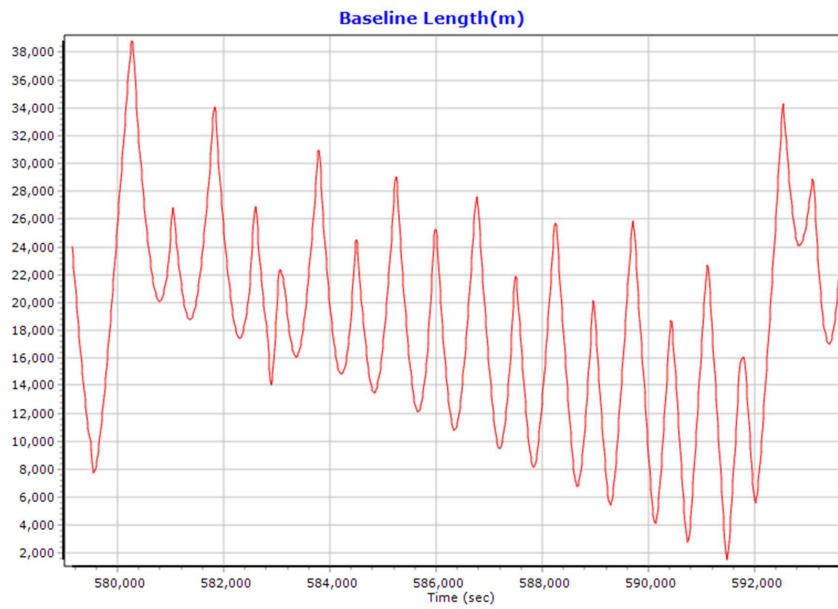
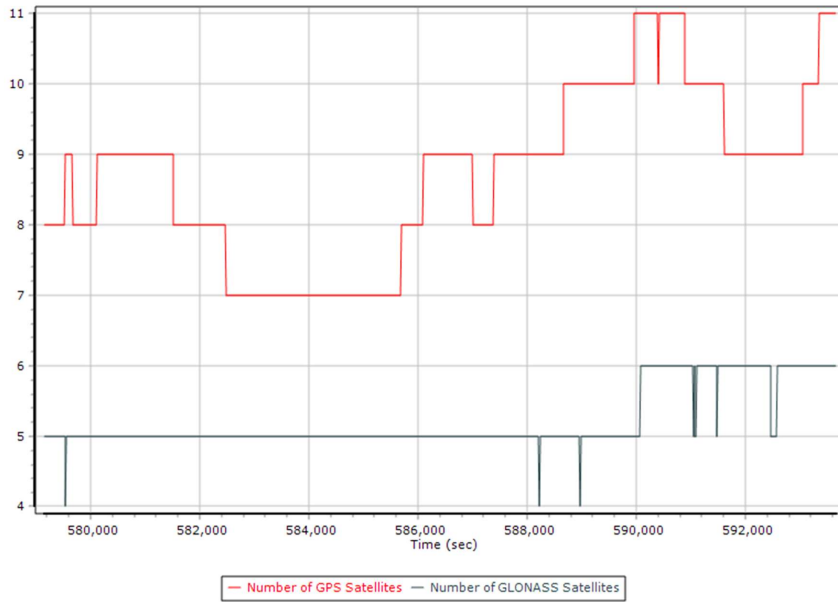
Standard Deviation <3cm 10cm 50cm 1m 10m

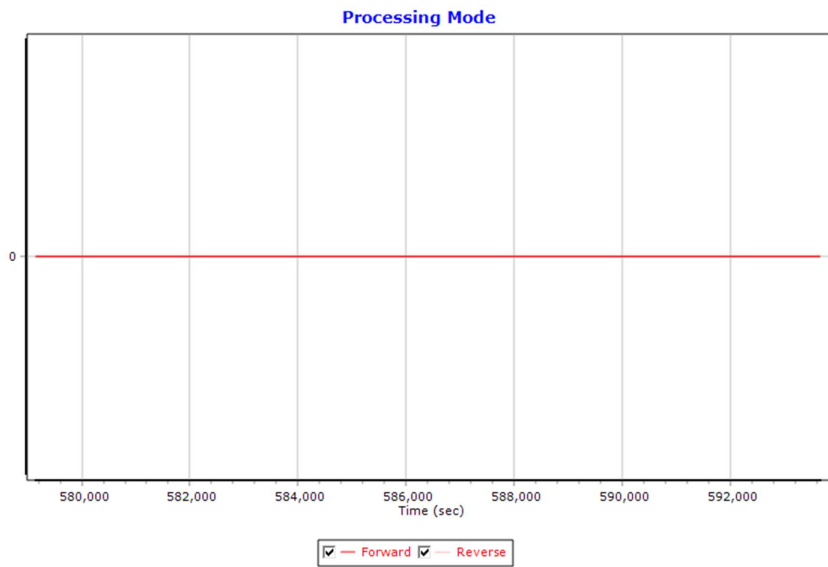
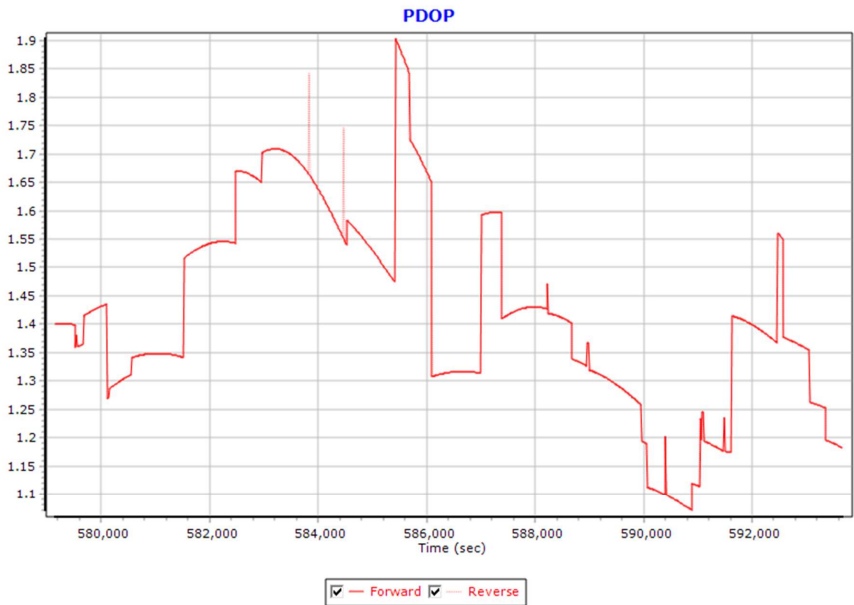
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.



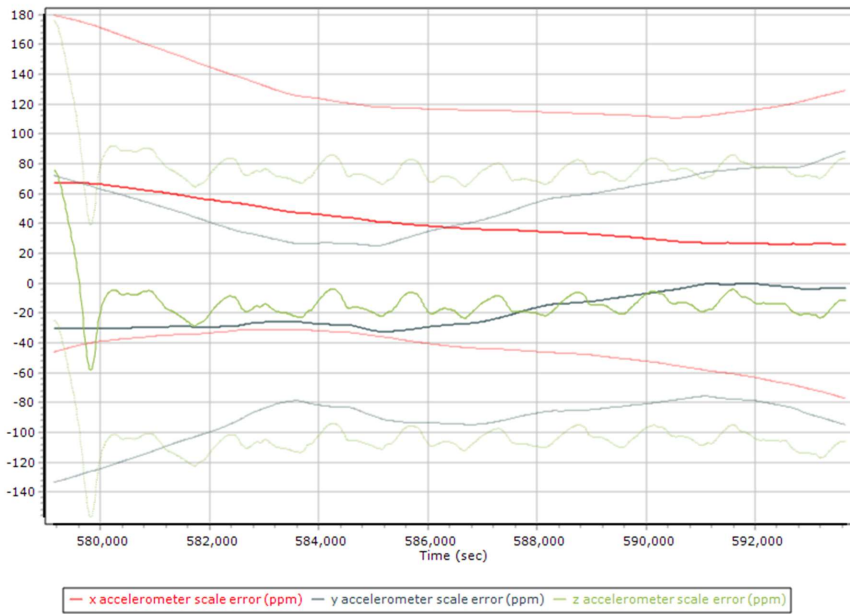
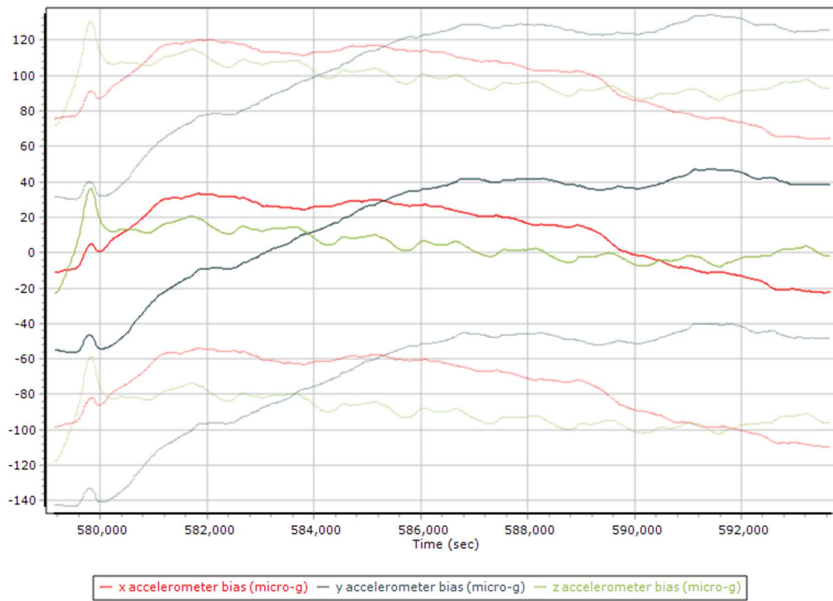


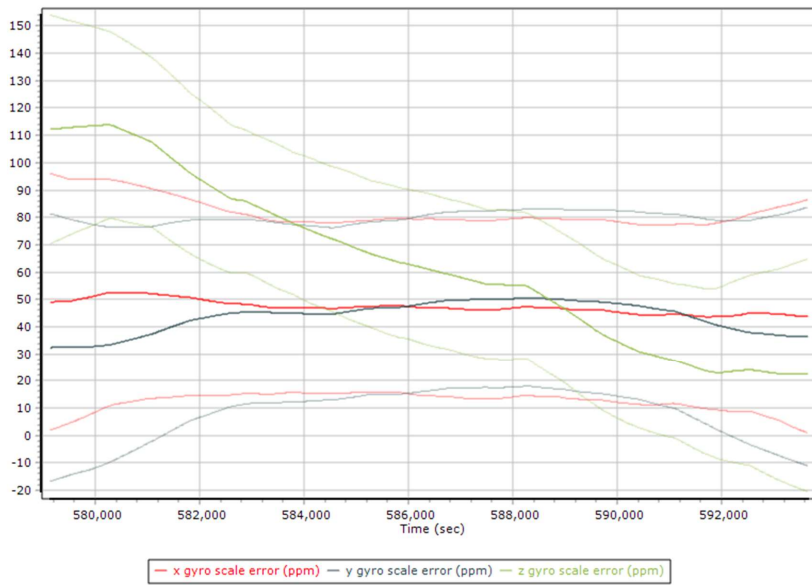
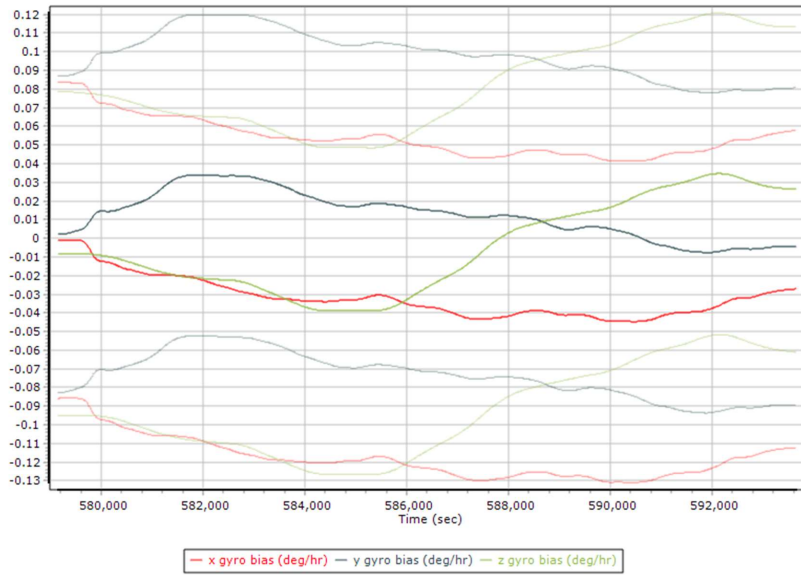




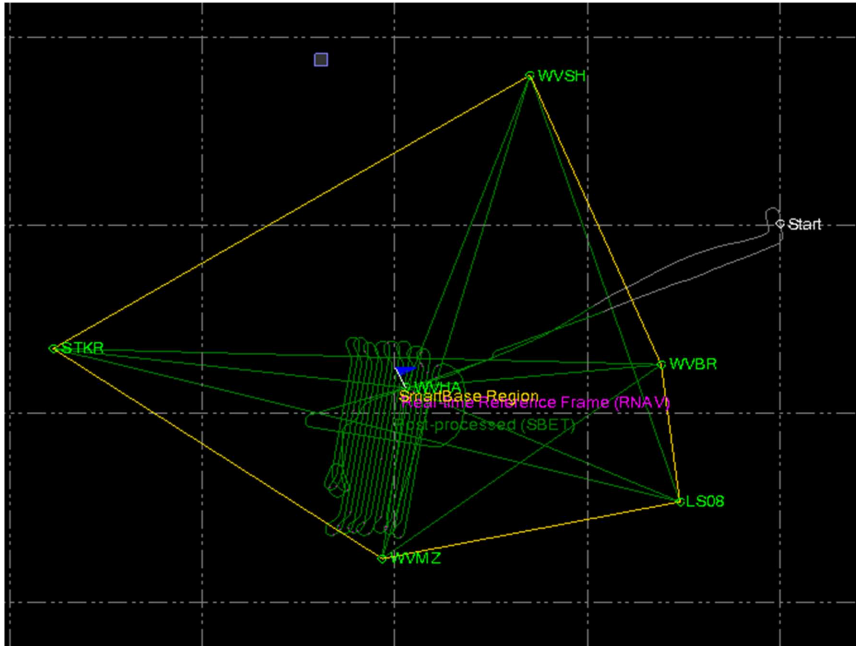


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR





45A19083A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

| | | | |
|--------------------------------------------|---------------------------------------|----------------------------------------------|----------------------------------------|
| Stabilized Mount to IMU Lever Arm | | Stabilized Mount to IMU Mounting Angles | |
| X | <input type="text" value="-0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.010 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.352 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Stabilized Mount to Primary GNSS Lever Arm | | Aircraft to Stabilized Mount Mounting Angles | |
| X | <input type="text" value="-0.049 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.003 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-1.230 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | <input type="text" value="3cm"/> | | |
| | <3cm 10cm 50cm 1m 10m | | |

Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

Project Settings [X]

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing**
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles

Timing

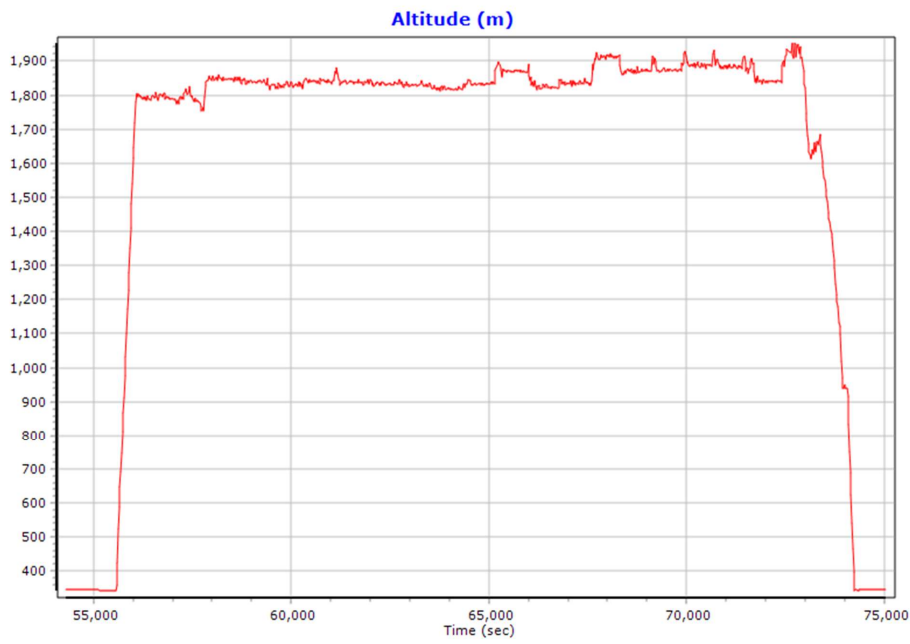
Start: 56586.000 Data: Incr. (sec) ^

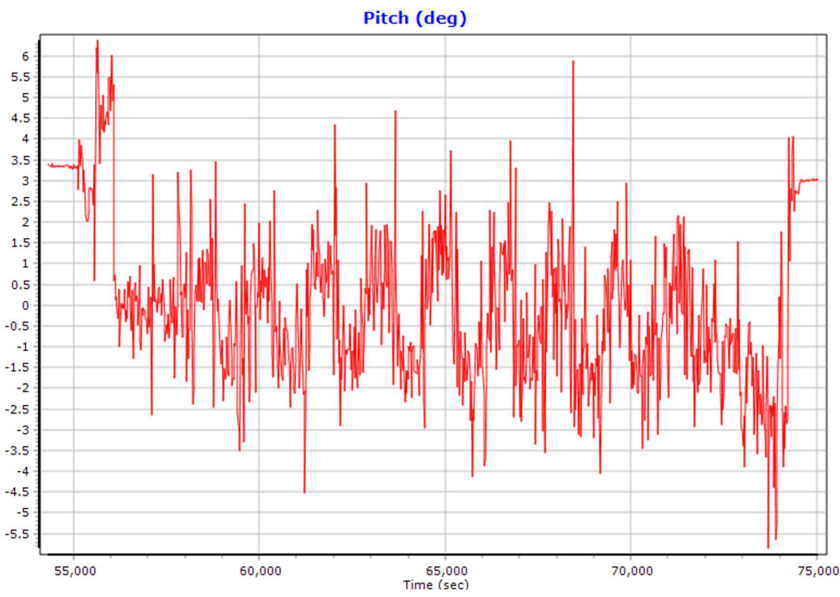
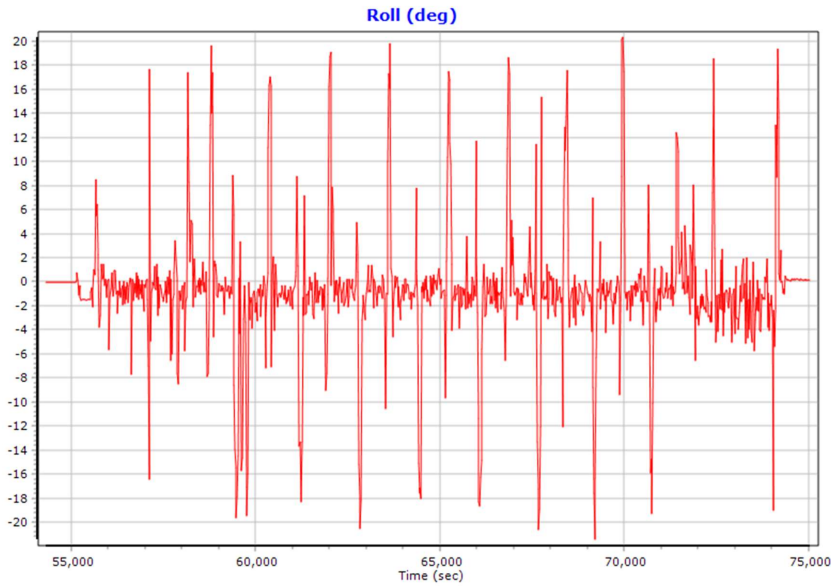
End: 73409.000 Output Record: 0.005000

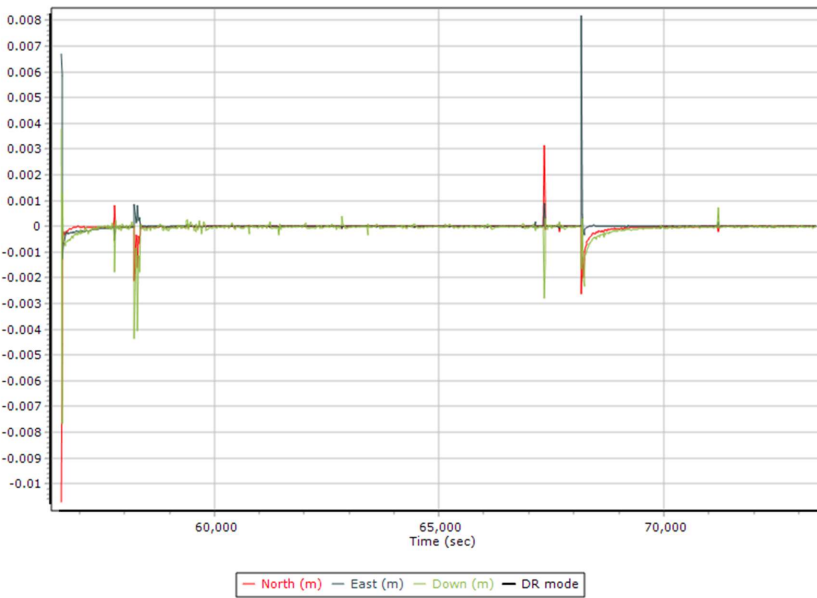
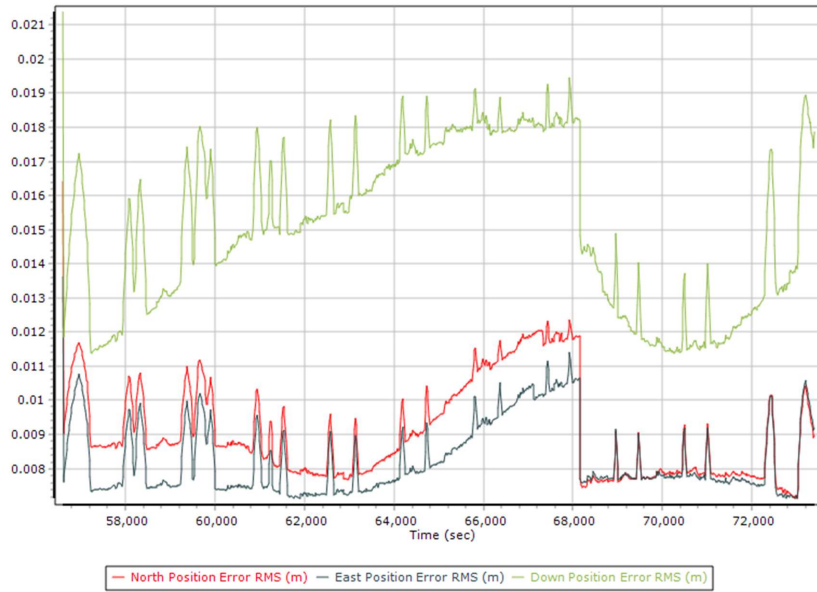
Entire time interval IMU: 0.005000

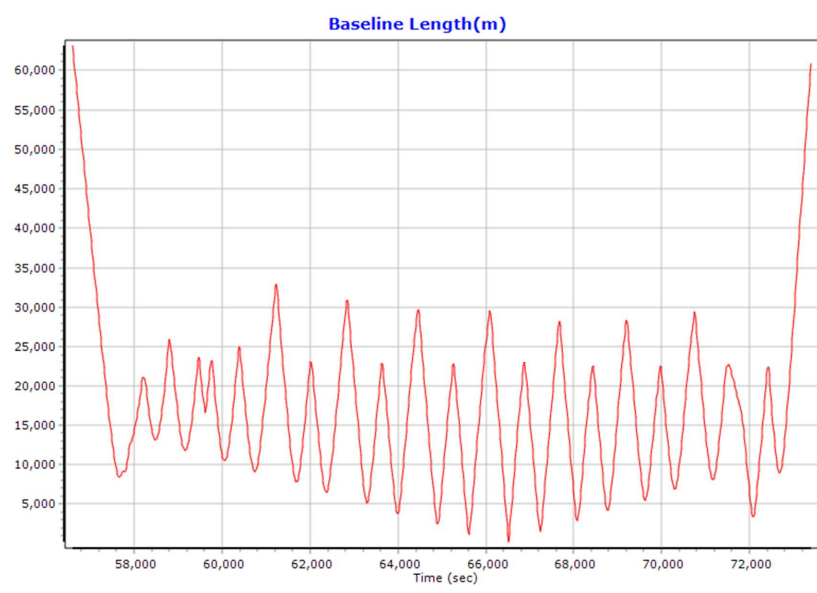
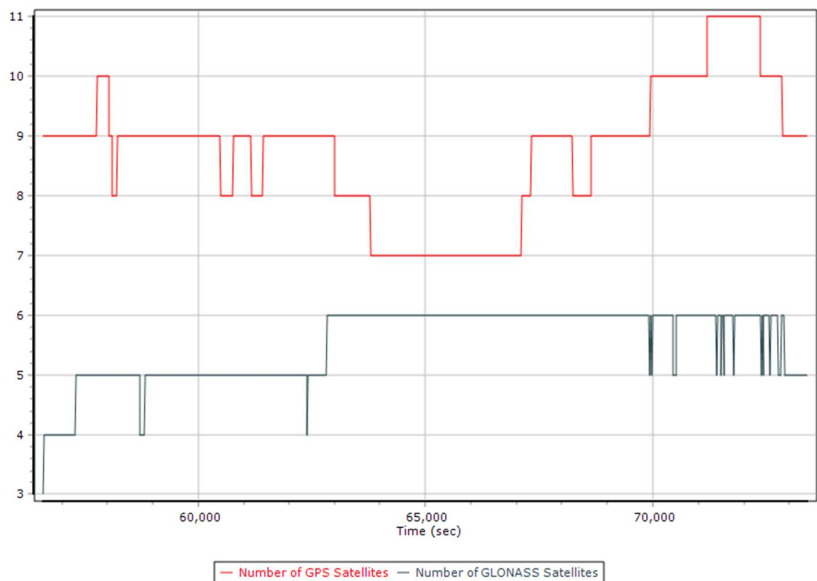
Seconds of start week Primary GNSS: 1.000000 v

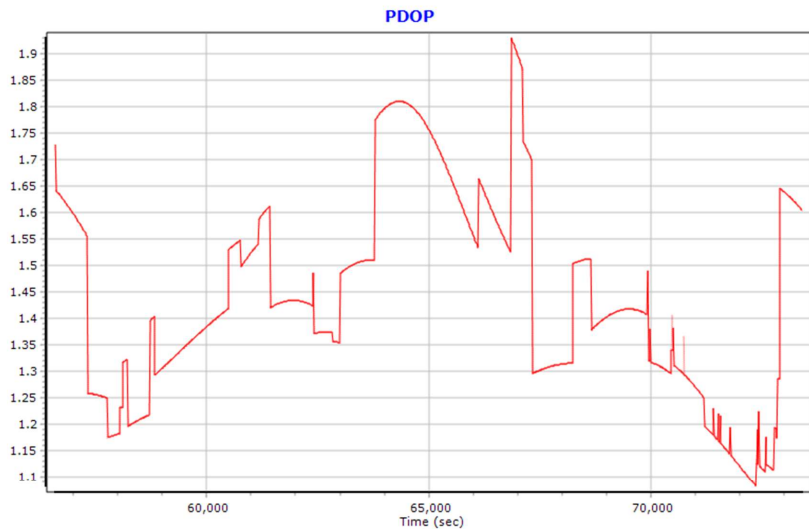
UTC Offset: 18.000



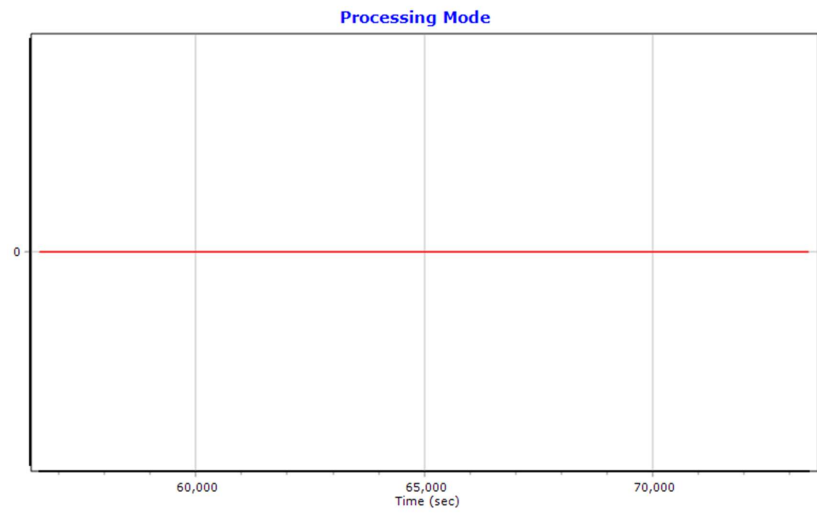






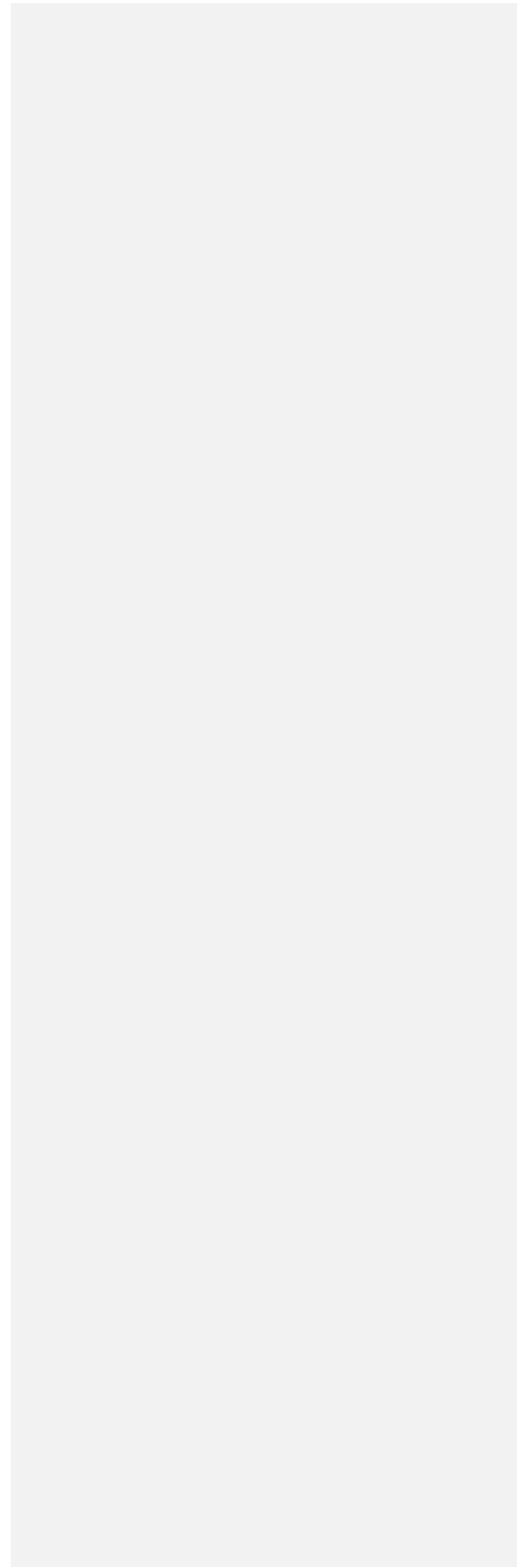


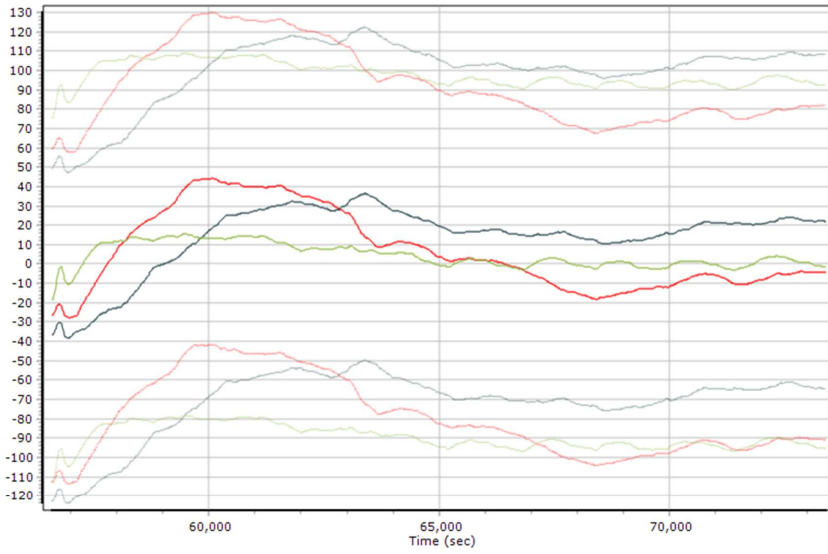
Forward Reverse



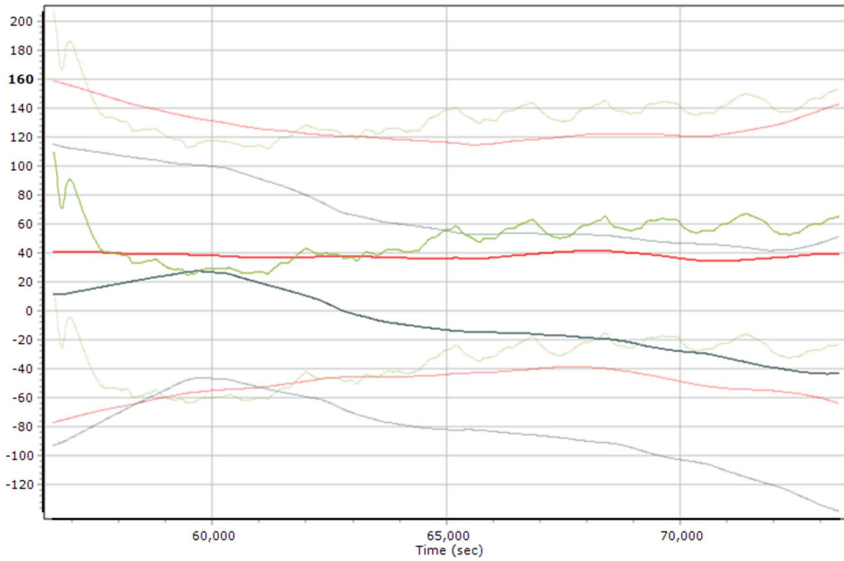
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

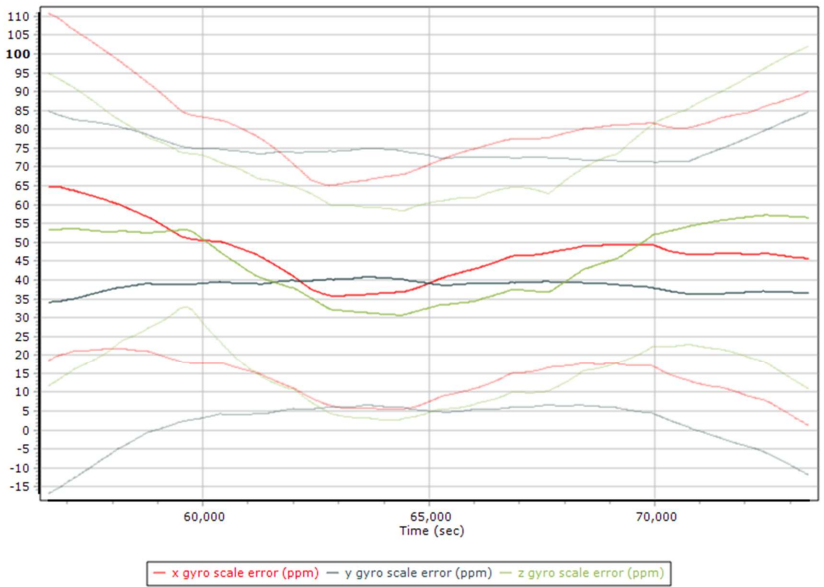
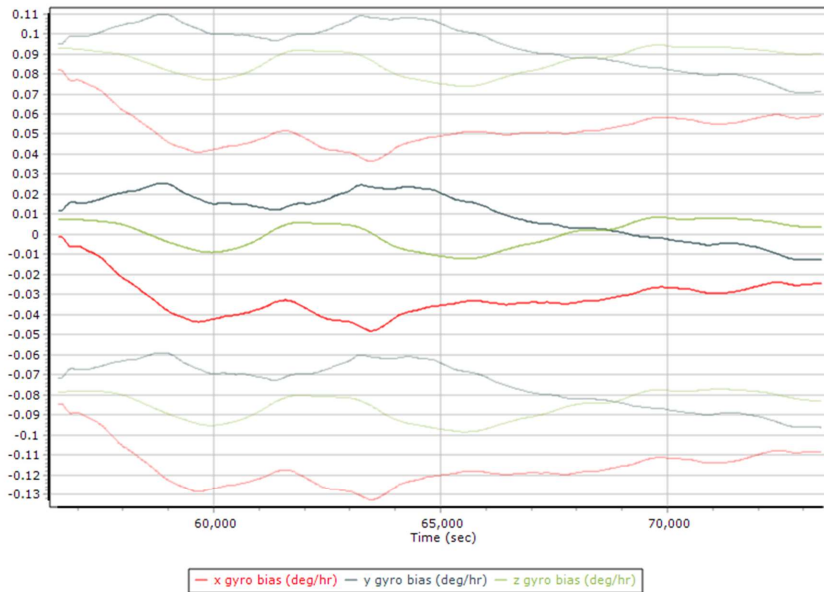




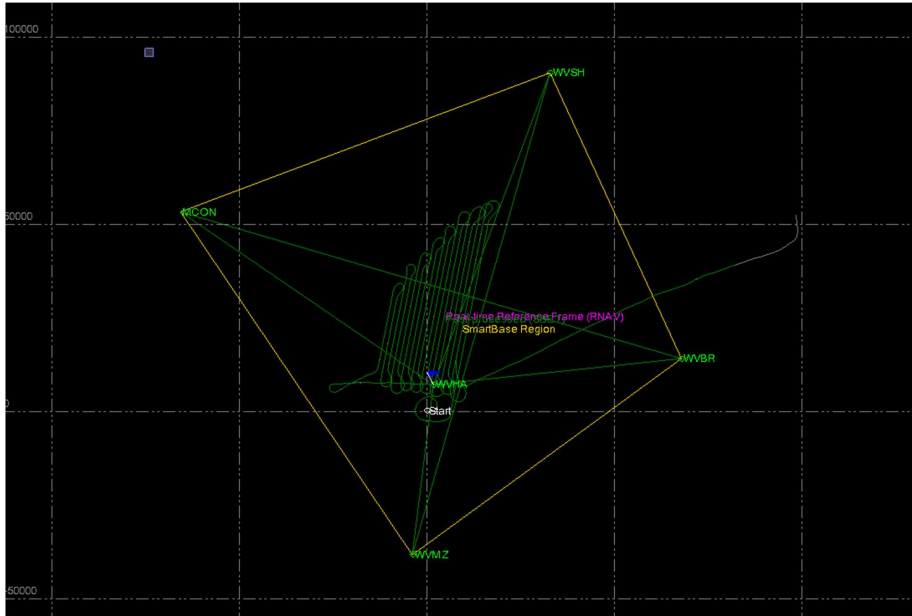
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



45A19085A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LIDAR
- SAR

| Stabilized Mount to IMU Lever Arm | Stabilized Mount to IMU Mounting Angles |
|-----------------------------------|-----------------------------------------|
| X: -0.034 m | X: 0.000 deg |
| Y: -0.010 m | Y: 0.000 deg |
| Z: -0.352 m | Z: 0.000 deg |

| Stabilized Mount to Primary GNSS Lever Arm | Aircraft to Stabilized Mount Mounting Angles |
|--------------------------------------------|----------------------------------------------|
| X: -0.049 m | X: 0.000 deg |
| Y: 0.003 m | Y: 0.000 deg |
| Z: -1.230 m | Z: 0.000 deg |

Standard Deviation: <3cm 10cm 50cm 1m 10m

Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
- Timing
- Algorithms
- Initialization

Timing

Start 225800.000

End 240000.000

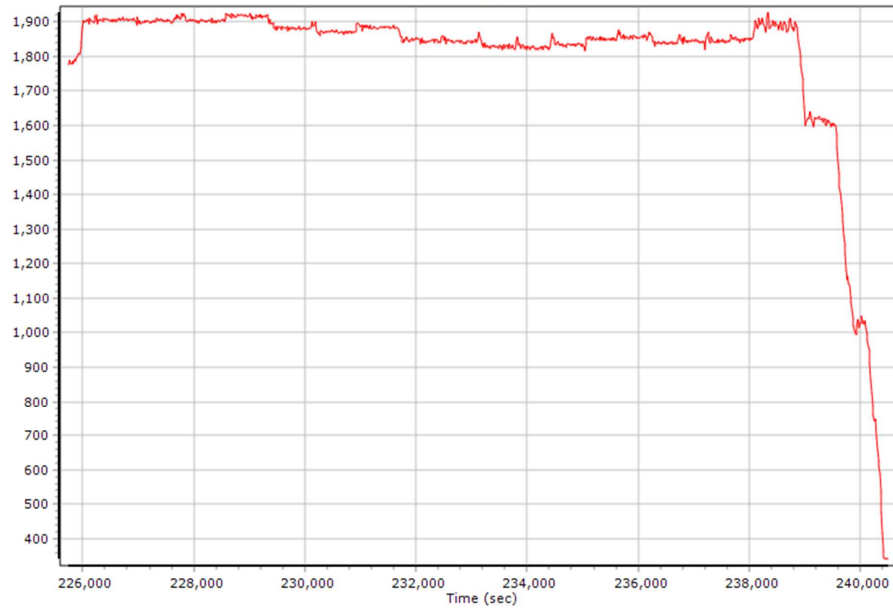
Entire time interval

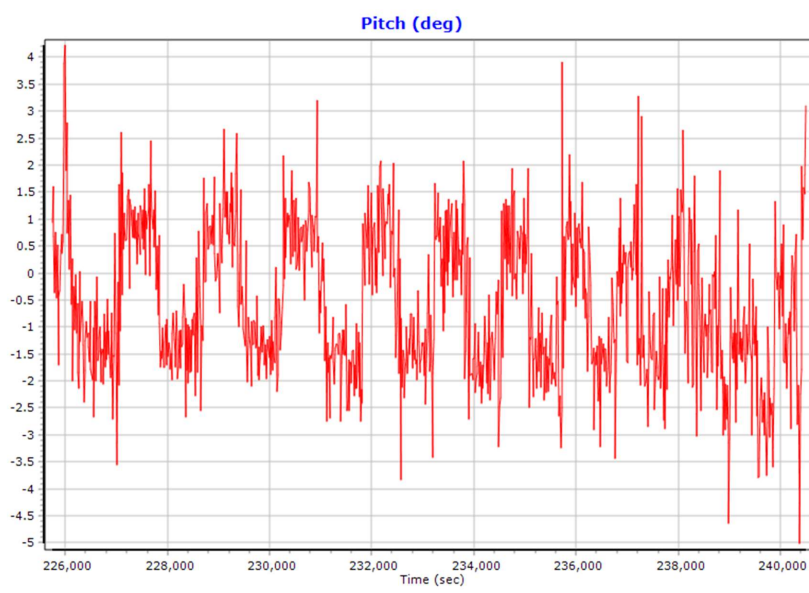
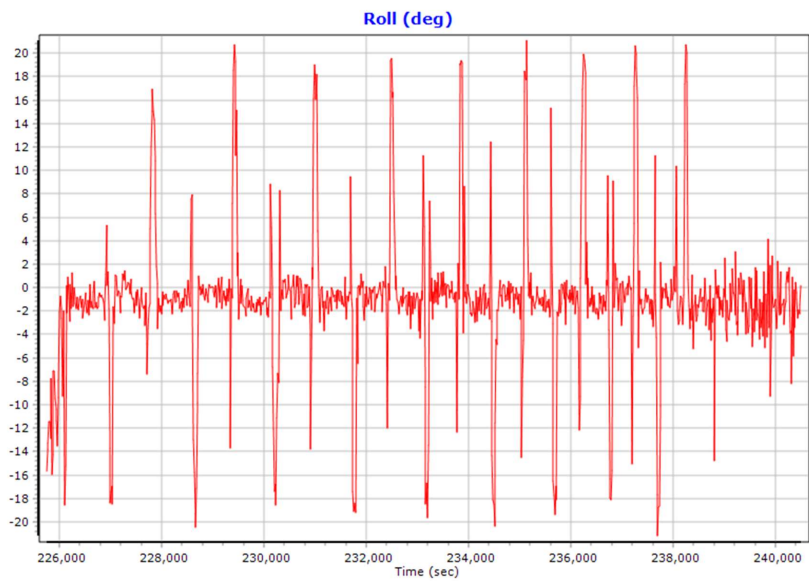
Seconds of start week

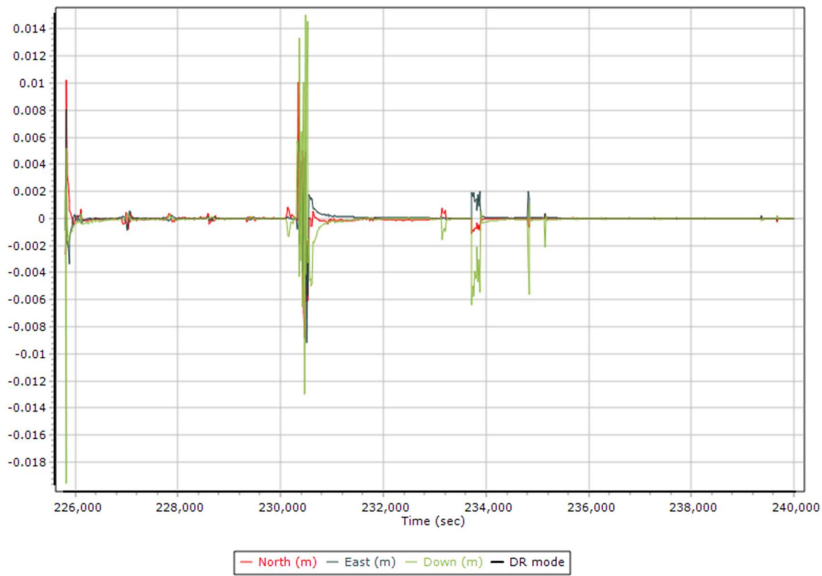
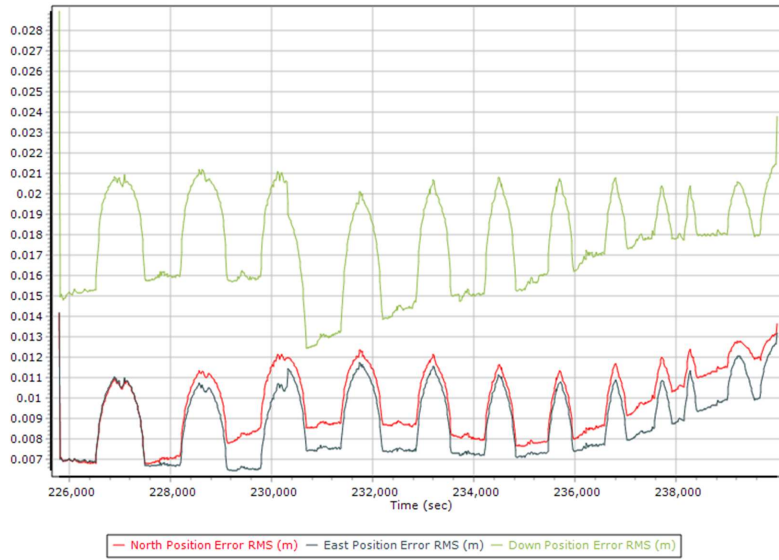
UTC Offset 18.000

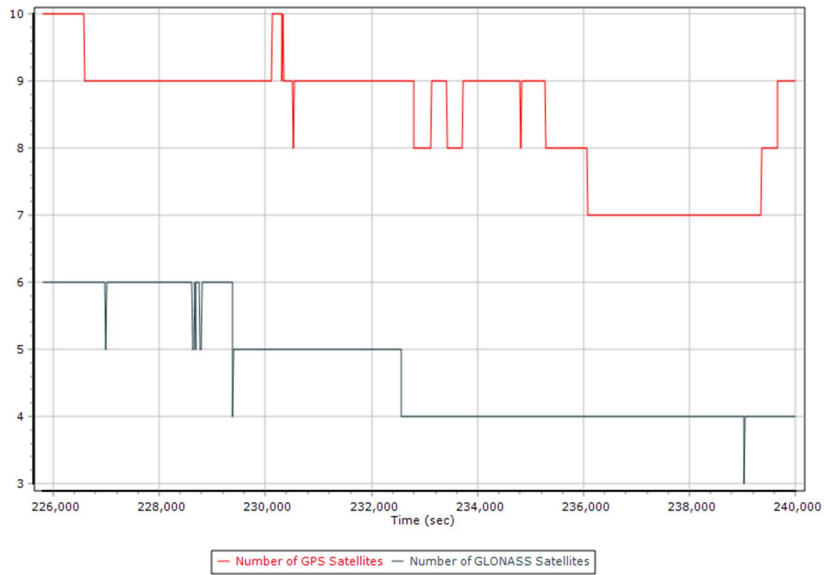
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

Altitude (m)

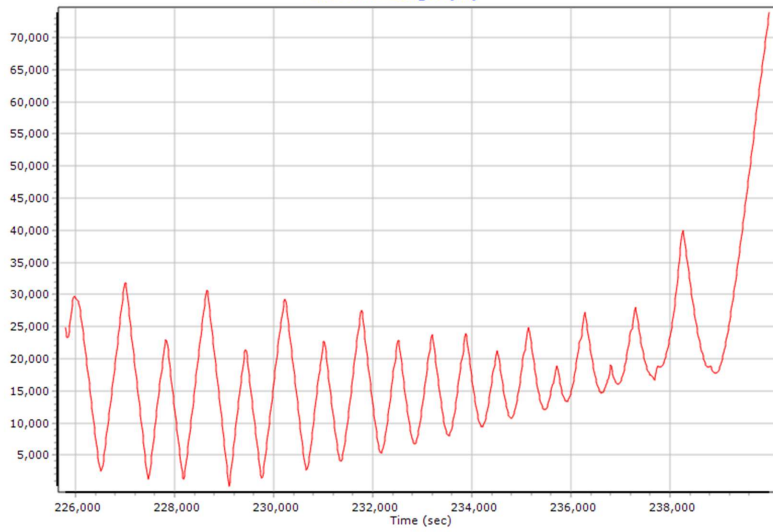




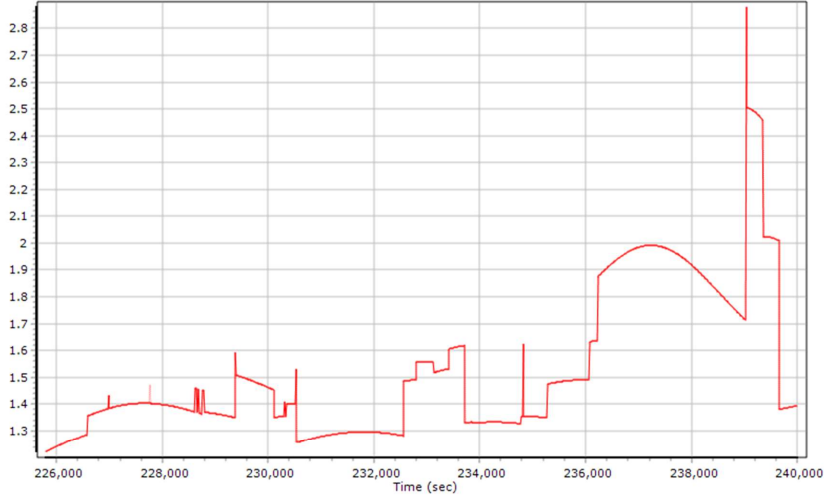




Baseline Length(m)

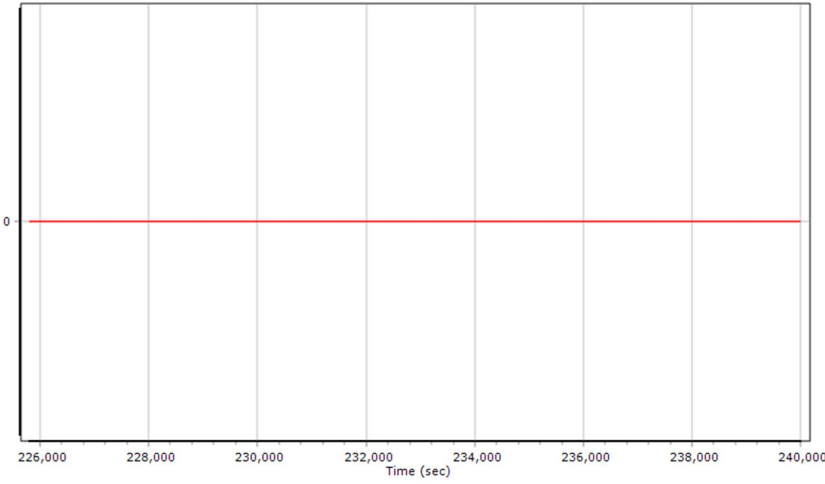


PDOP



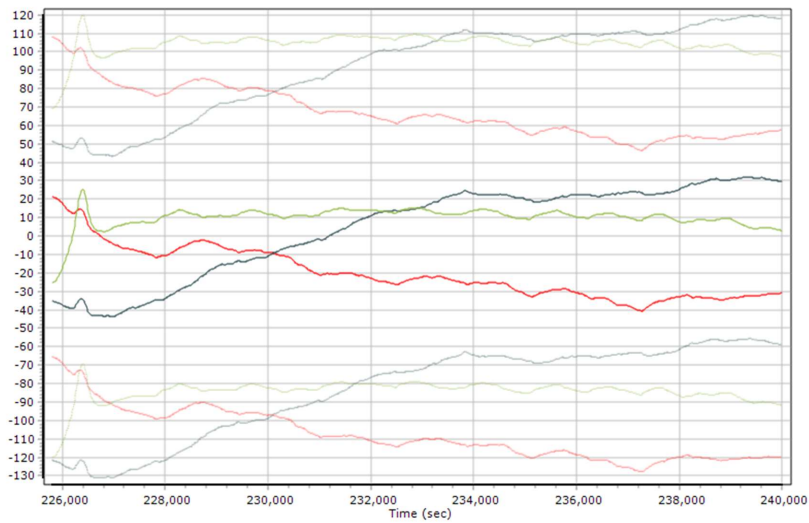
Forward Reverse

Processing Mode

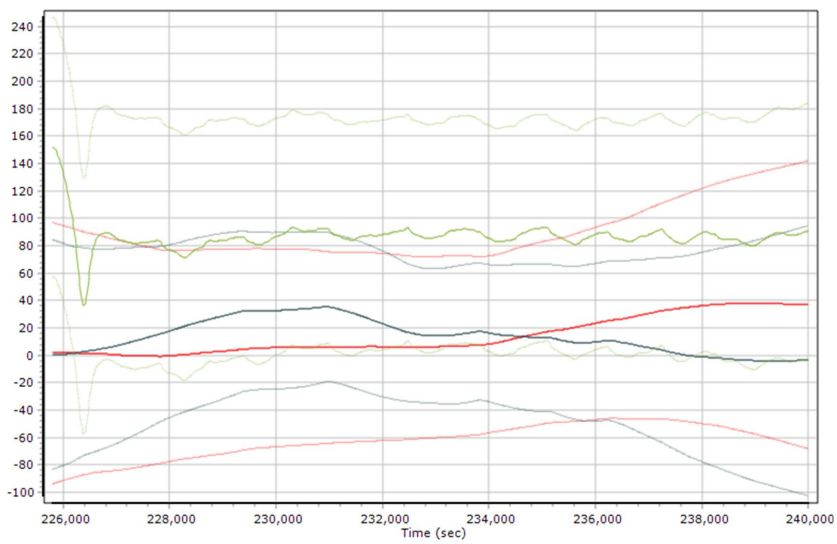


Forward Reverse

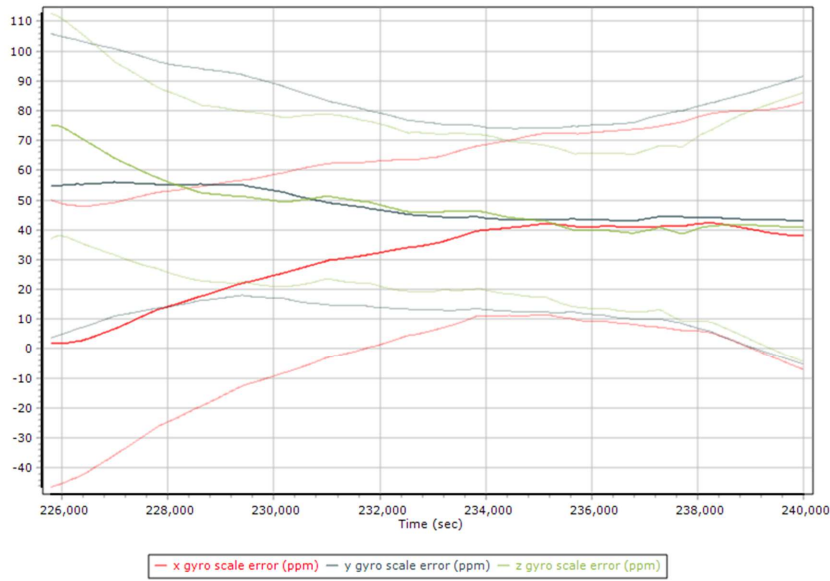
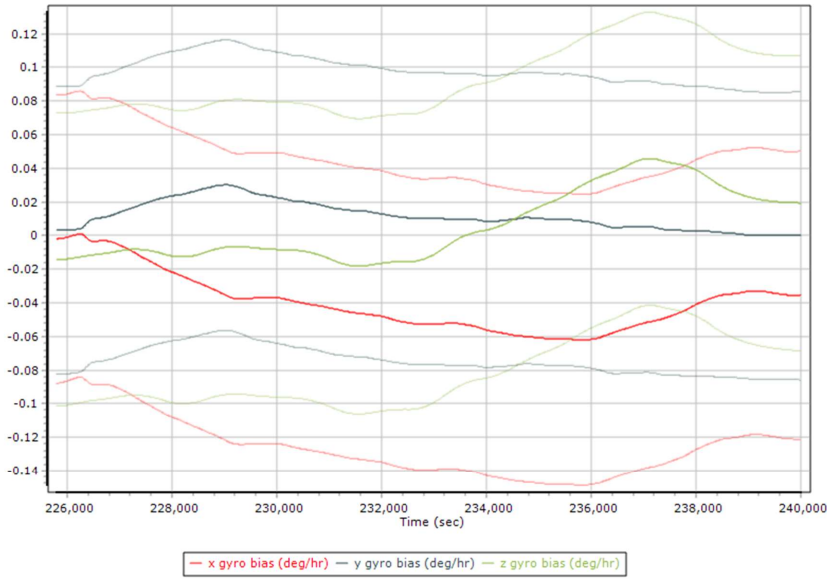
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



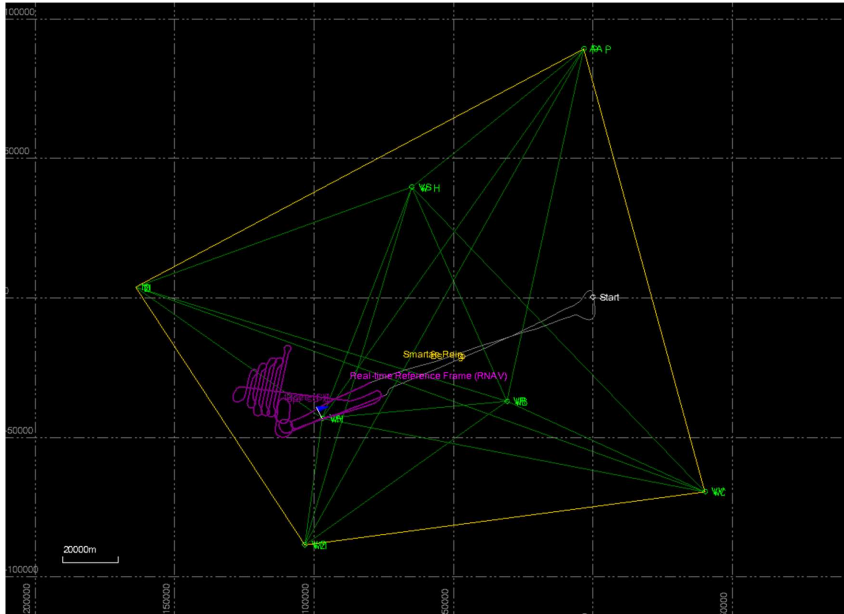
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

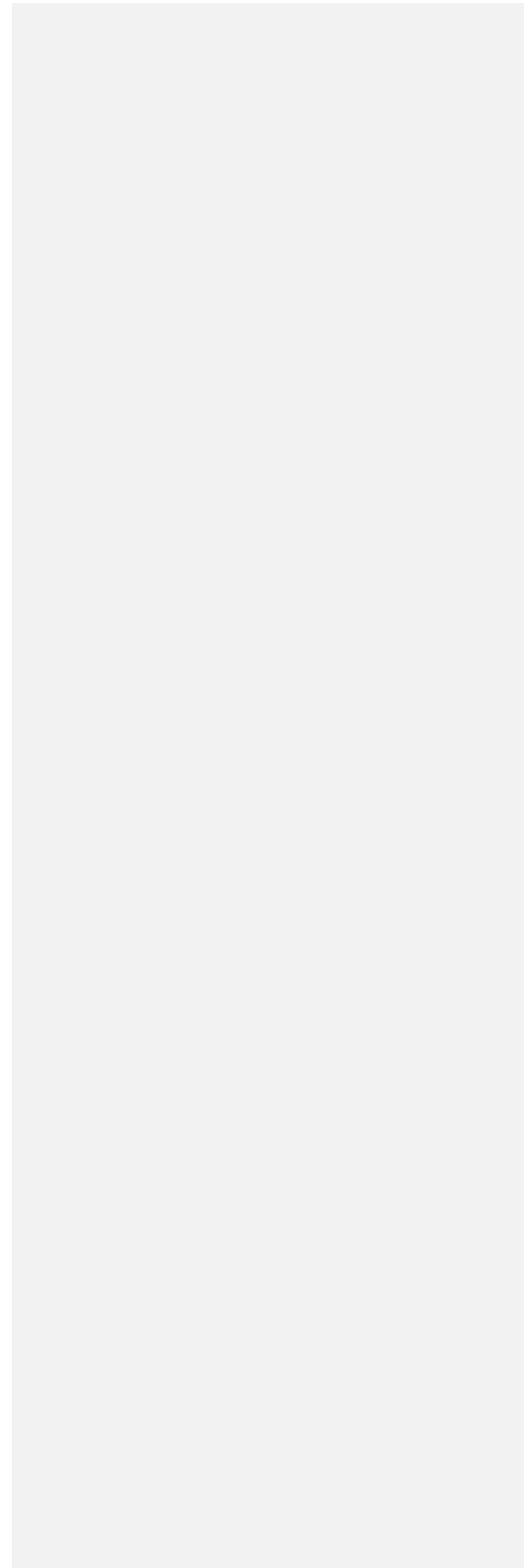


45A19085B



- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
 - Export
 - Camera
 - LiDAR
 - SAR

| | | | |
|--------------------------------------------------------------------------------------------------------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|-----------------------------------------------------|-----------|
| Stabilized Mount to IMU Lever Arm | | Stabilized Mount to IMU Mounting Angles | |
| X | -0.034 m | X | 0.000 deg |
| Y | -0.010 m | Y | 0.000 deg |
| Z | -0.352 m | Z | 0.000 deg |
| Stabilized Mount to Primary GNSS Lever Arm | | Aircraft to Stabilized Mount Mounting Angles | |
| X | -0.049 m | X | 0.000 deg |
| Y | 0.003 m | Y | 0.000 deg |
| Z | -1.230 m | Z | 0.000 deg |
| Standard Deviation | <div style="display: flex; align-items: center;"> <div style="width: 20px; height: 10px; background-color: #007bff; margin-right: 5px;"></div> <3cm 10cm 50cm 1m 10m </div> | | |
| Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position. | | | |



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing**
 - Algorithms
 - Initialization

Timing

Start: 250149.000

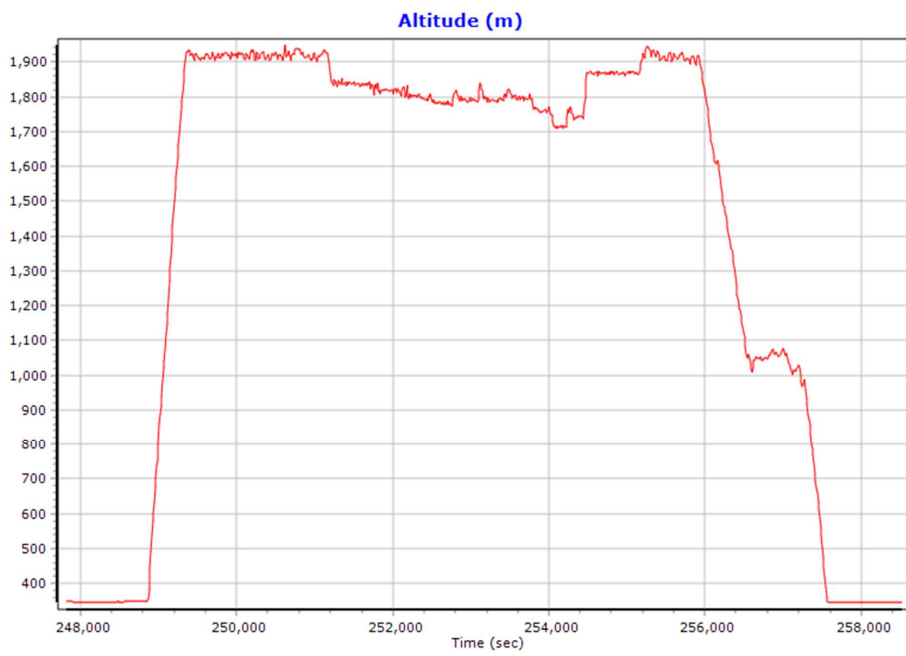
End: 256265.000

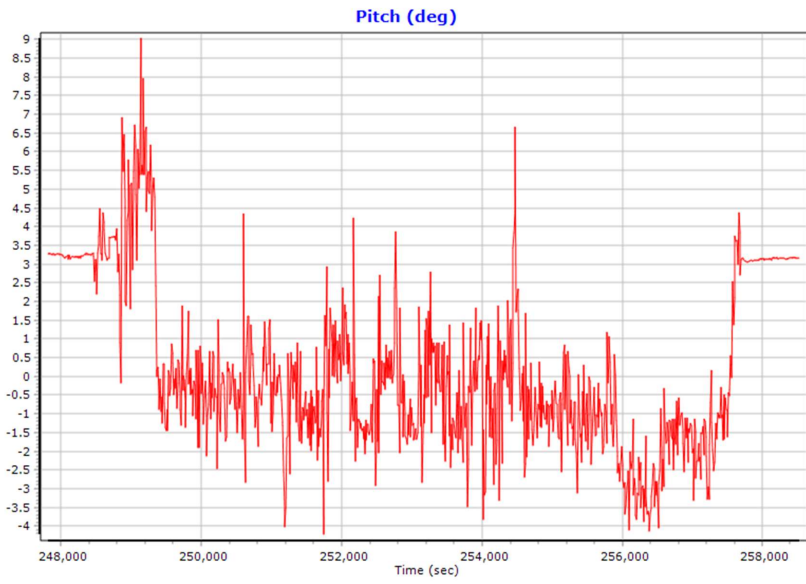
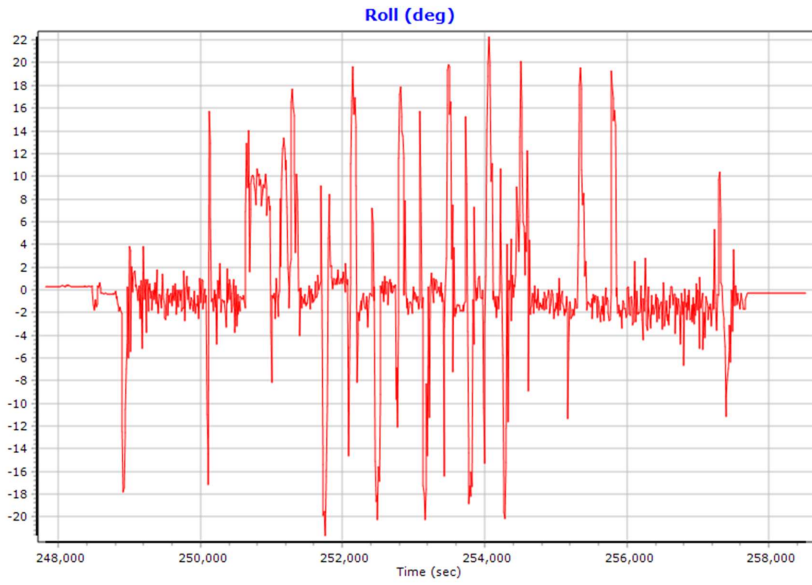
Entire time interval

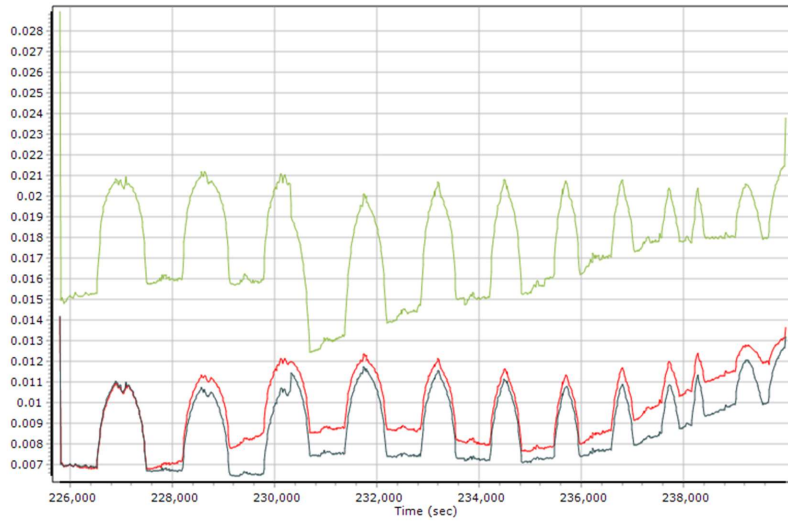
Seconds of start week

UTC Offset: 18.000

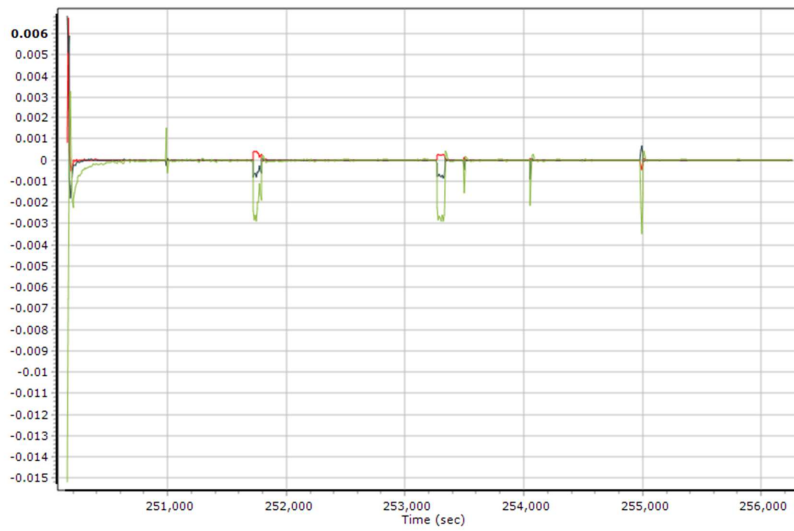
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |



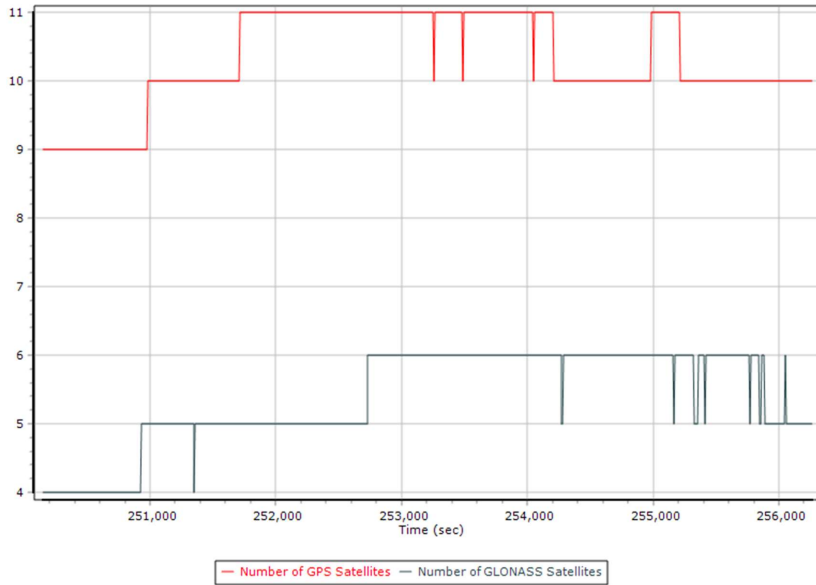




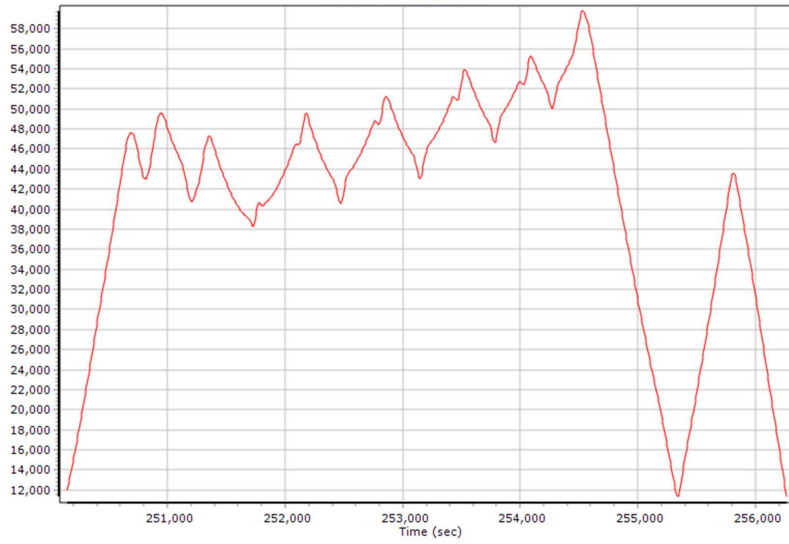
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



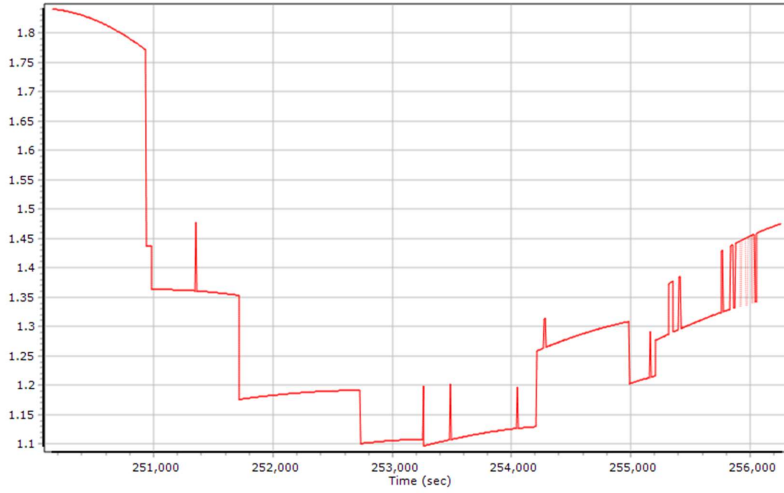
— North (m) — East (m) — Down (m) — DR mode



Baseline Length(m)

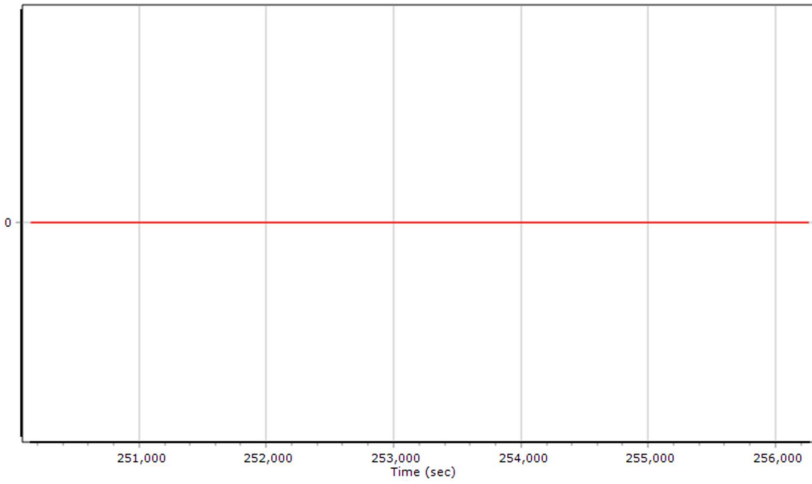


PDOP



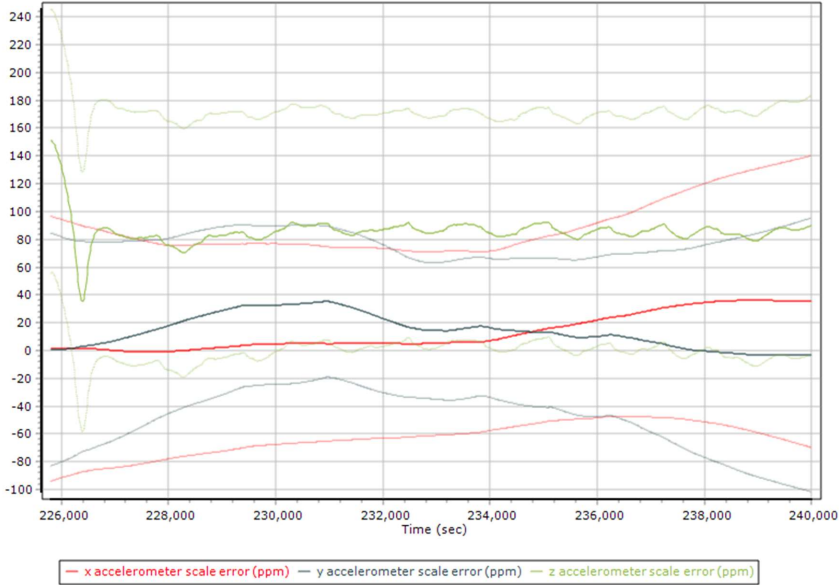
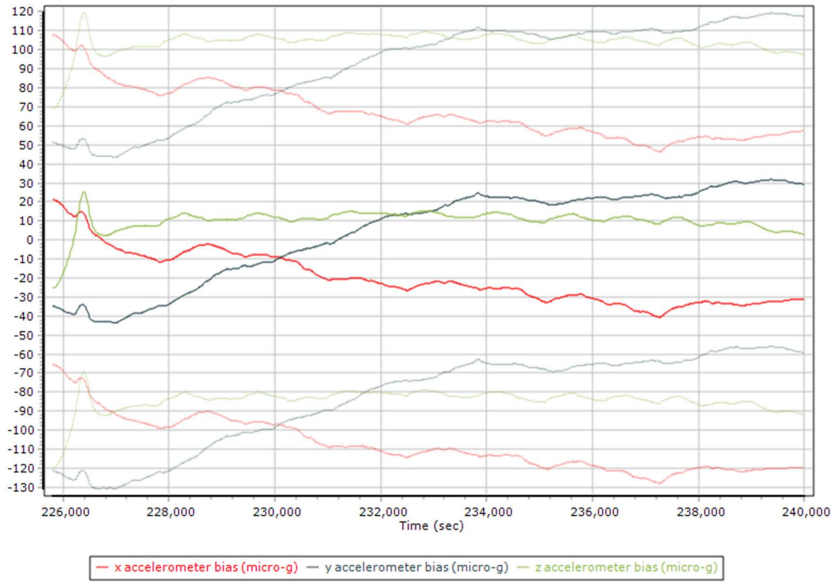
Forward Reverse

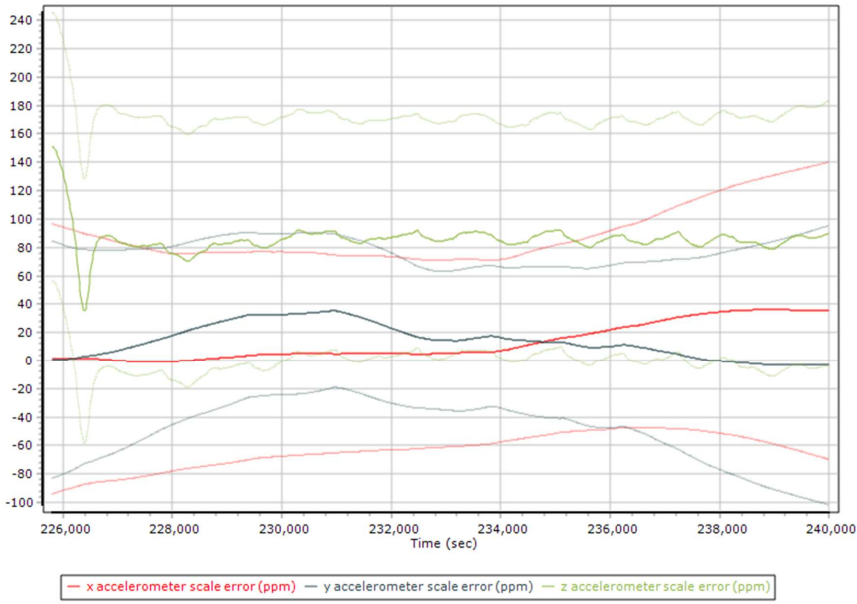
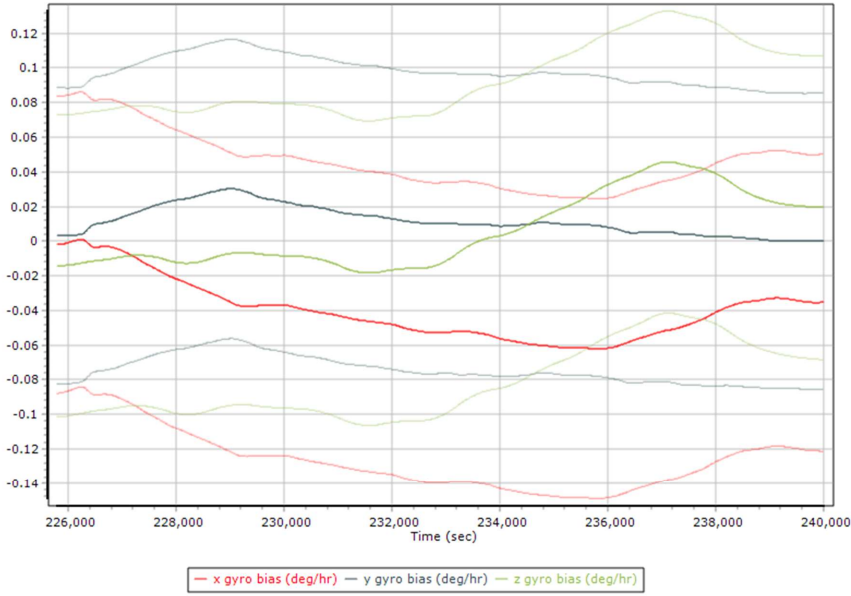
Processing Mode



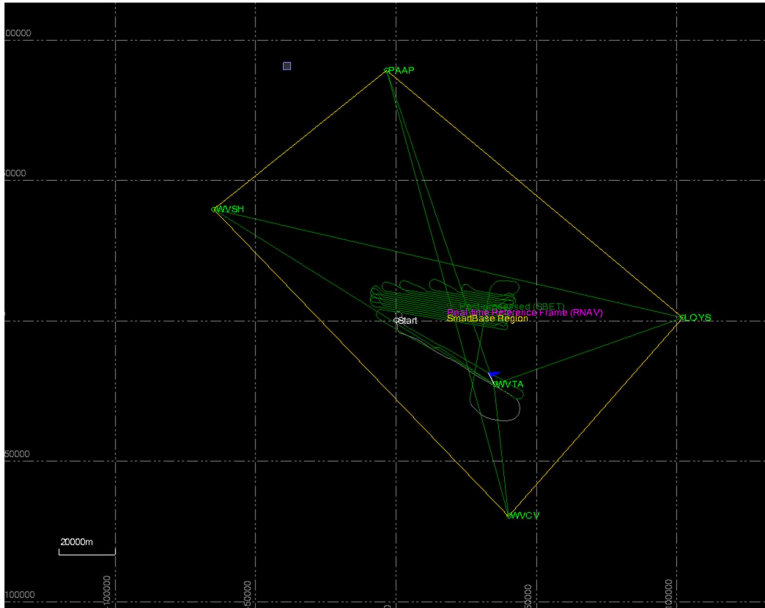
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR





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| | | | |
|--------------------------------------------------------------------------------------------------------|---------------------------------------|----------------------------------------------|----------------------------------------|
| Stabilized Mount to IMU Lever Arm | | Stabilized Mount to IMU Mounting Angles | |
| X | <input type="text" value="-0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.010 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.352 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Stabilized Mount to Primary GNSS Lever Arm | | Aircraft to Stabilized Mount Mounting Angles | |
| X | <input type="text" value="-0.049 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.003 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-1.230 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | | | |
| <input type="range" value="0.03"/> <3cm 10cm 50cm 1m 10m | | | |
| Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position. | | | |

Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing**
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR

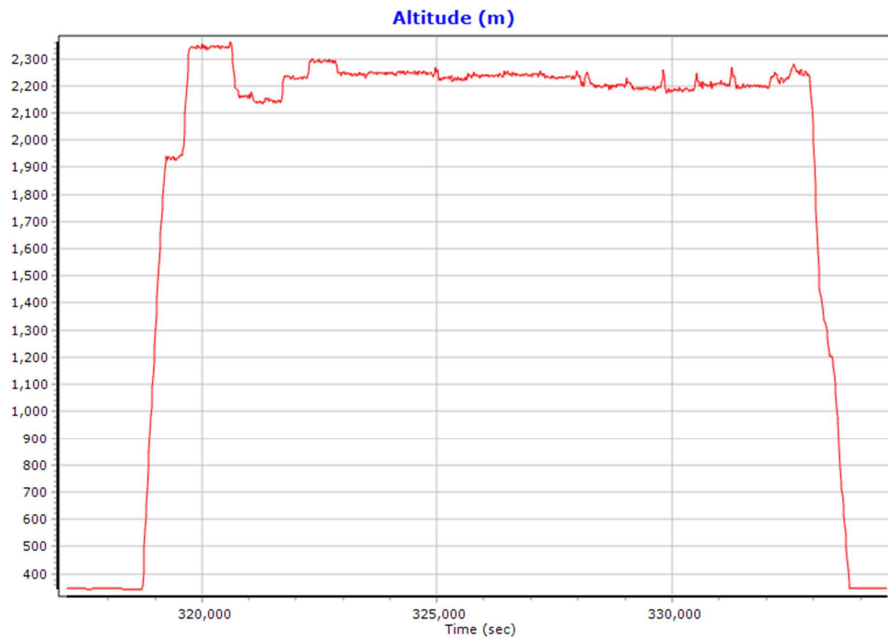
Timing

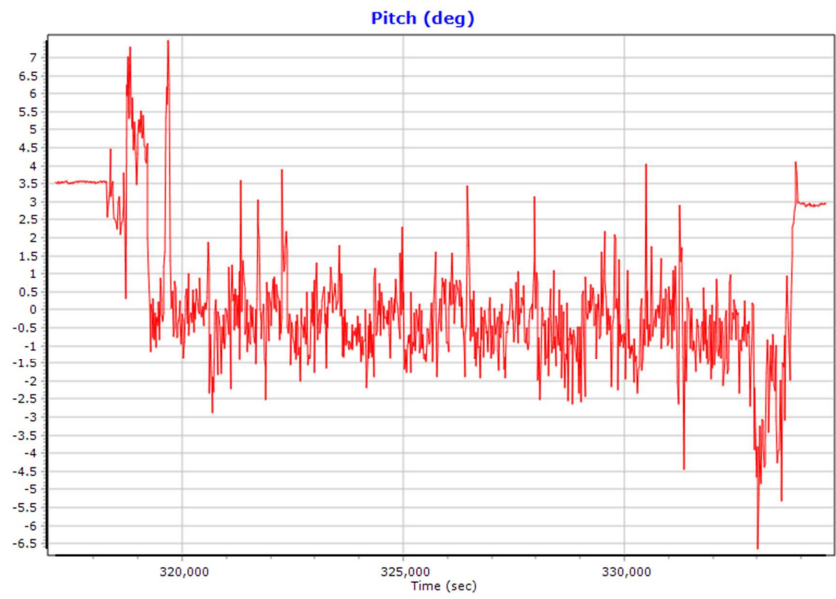
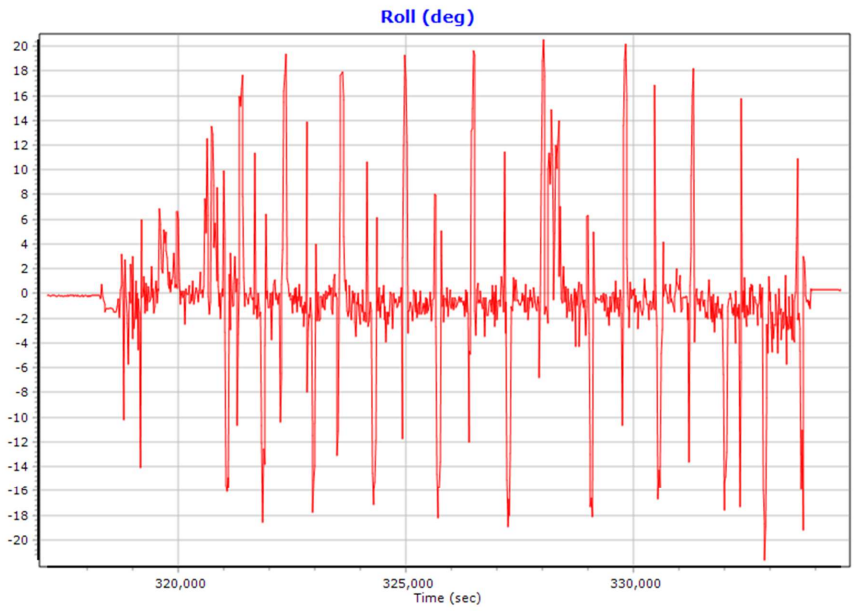
Start: 320000.000 End: 333591.647

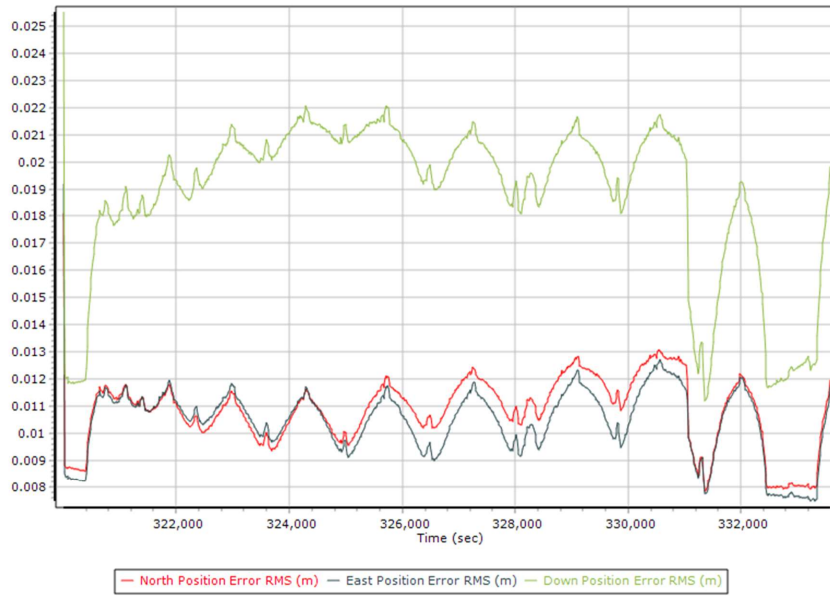
Entire time interval
 Seconds of start week

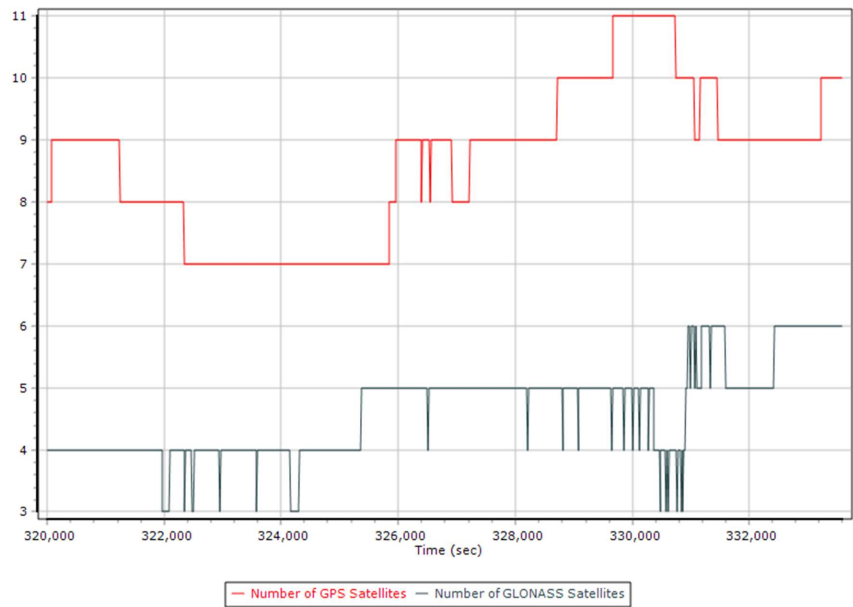
UTC Offset: 18.000

| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

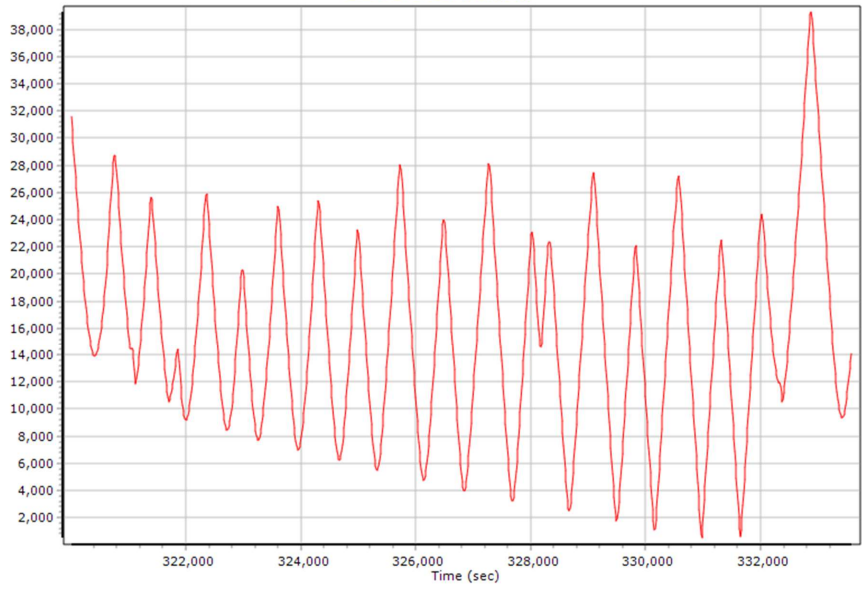




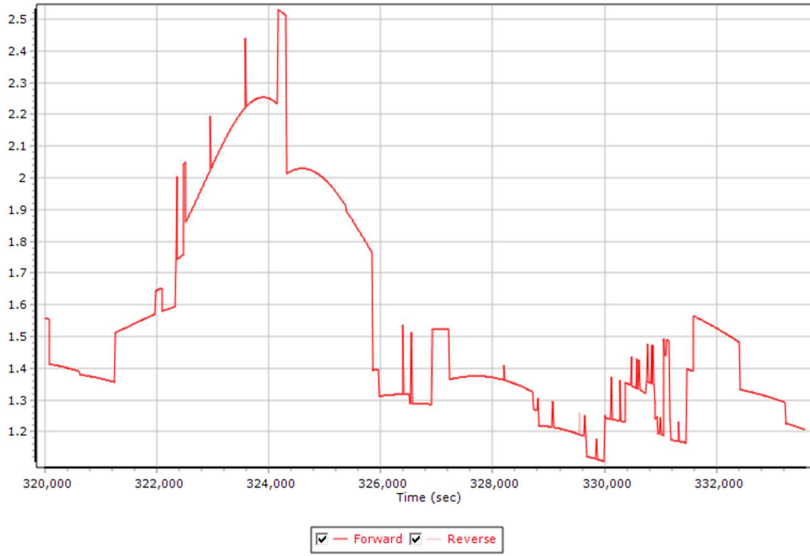




Baseline Length(m)

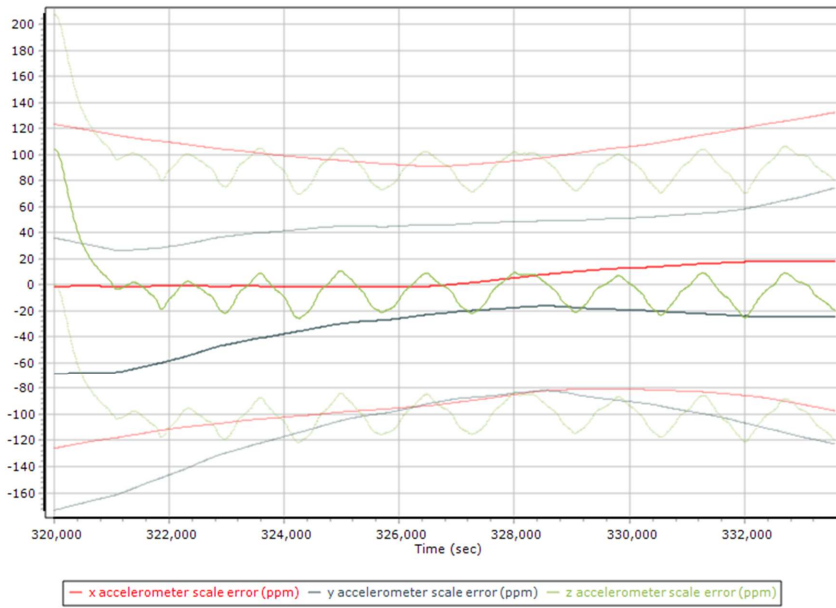
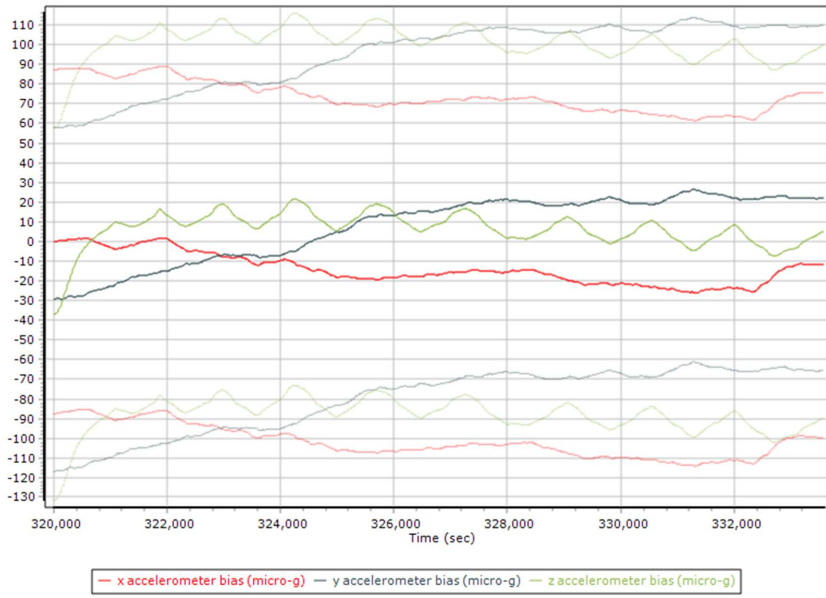


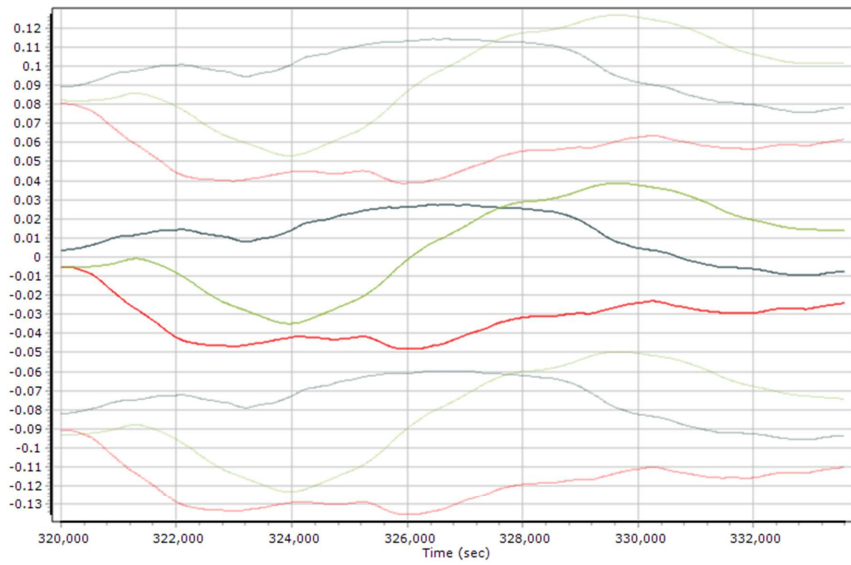
PDOP



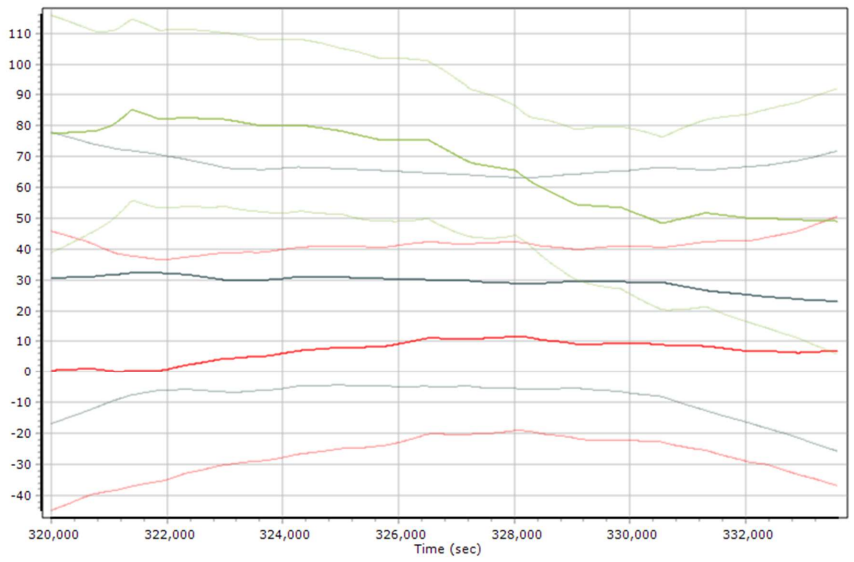
Processing Mode





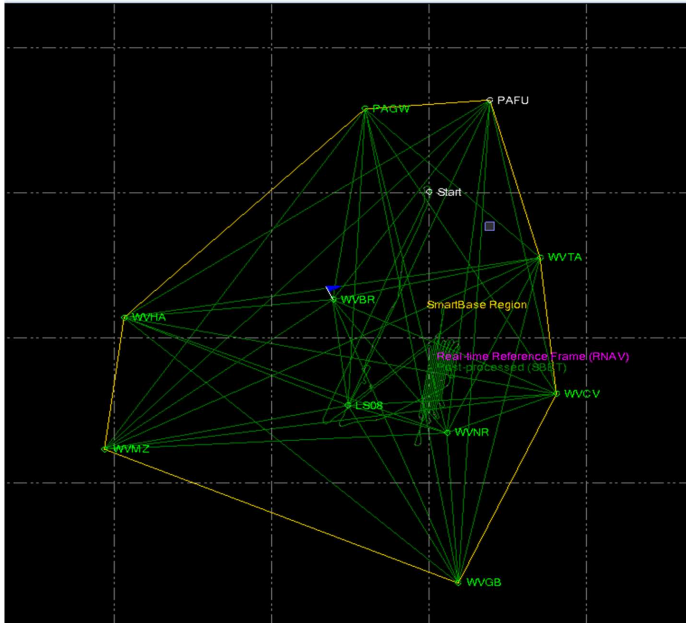


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

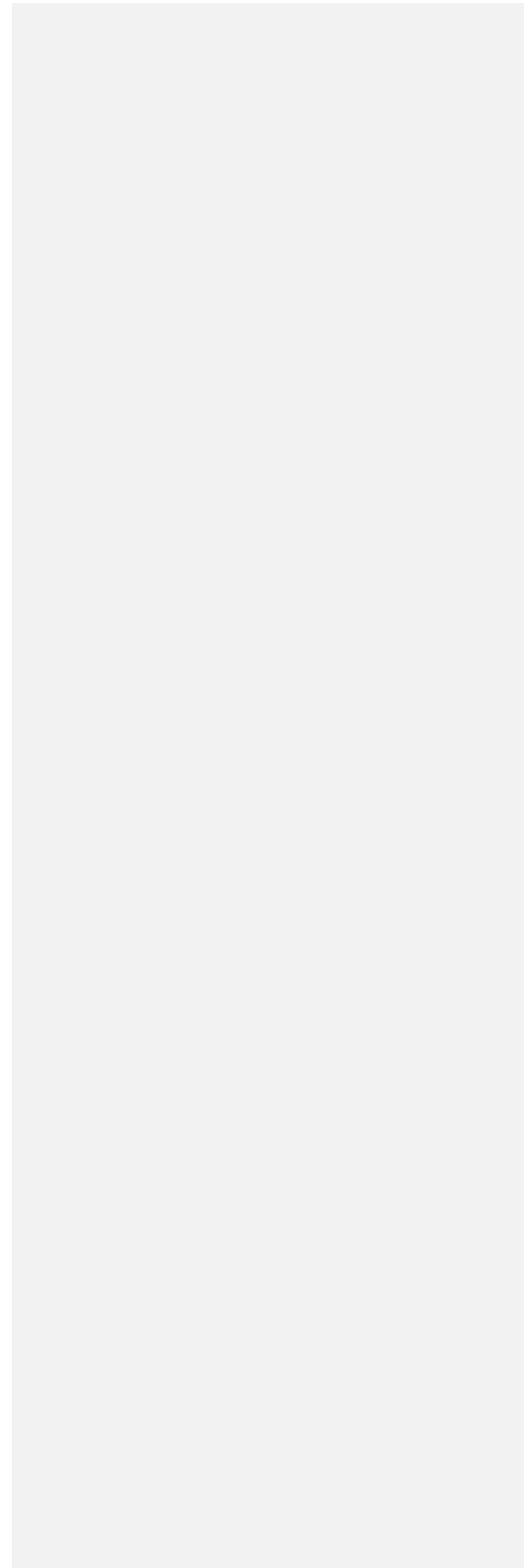


— x gyro scale error (ppm) — y gyro scale error (ppm) — z gyro scale error (ppm)

MNB18336A



| | | | |
|-----------------------------------------|---------------------------------------|---------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.150 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.061 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.992 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | | | |
| <input type="range" value="0.034"/> | | | |
| <small><3cm 10cm 50cm 1m 10m</small> | | | |



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera

Timing

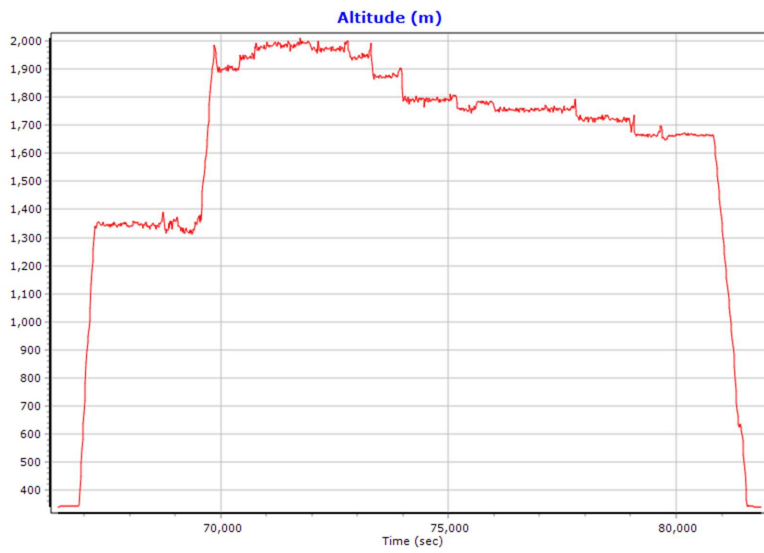
Start: 63416.000 Data Incr. (sec)

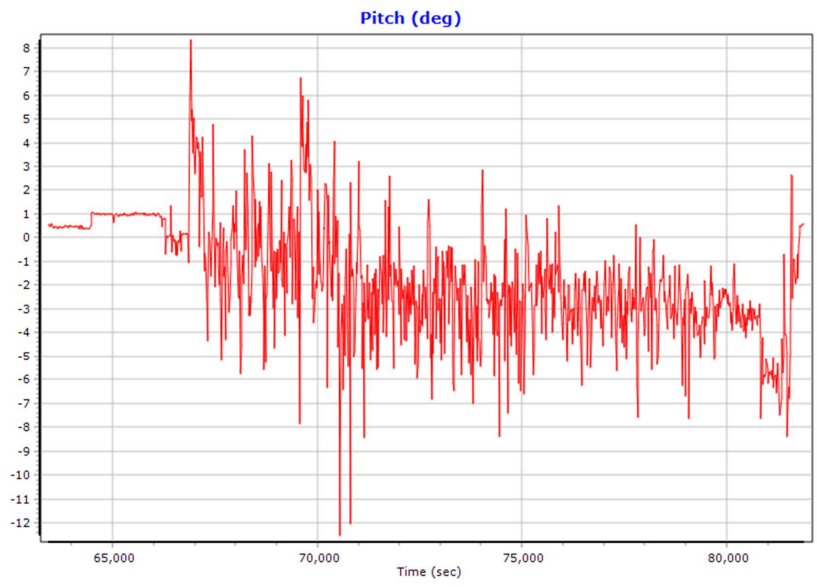
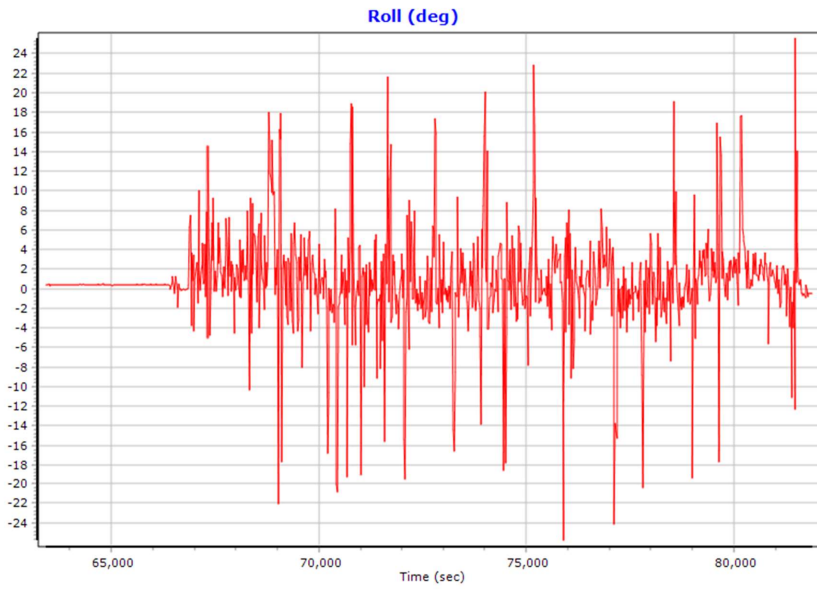
End: 81890.000 Output Record 0.005000

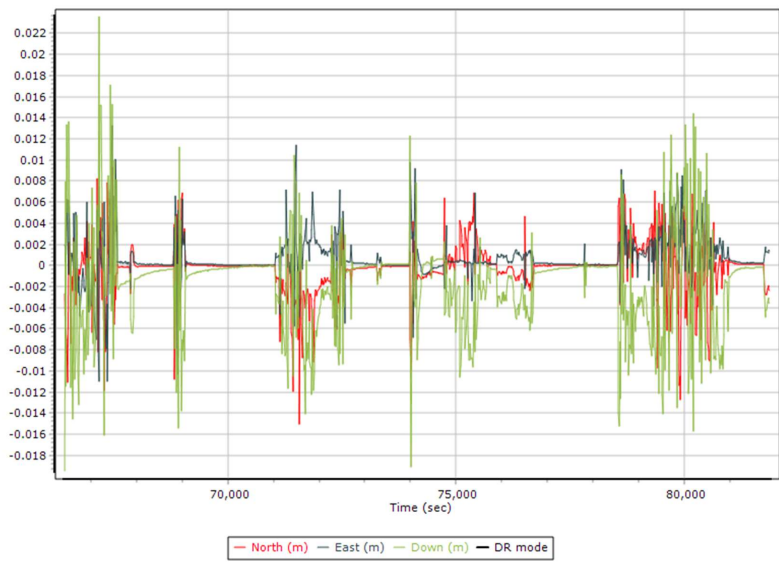
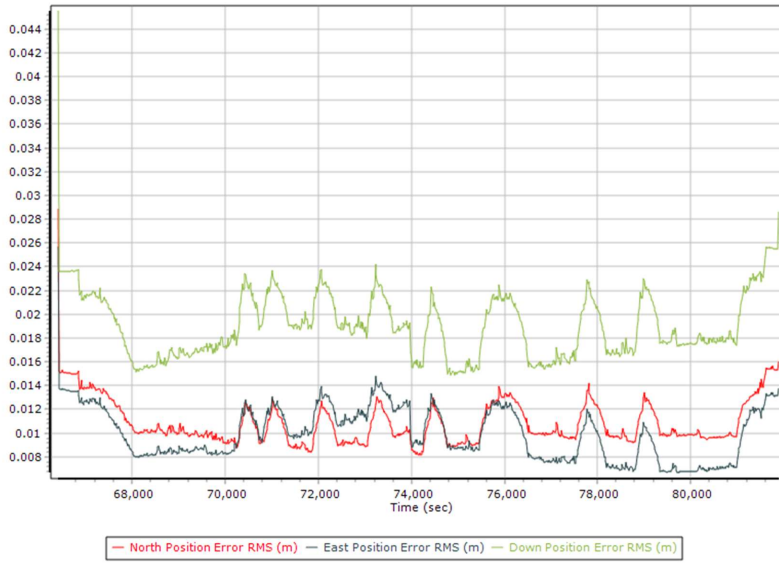
Entire time interval IMU 0.005000

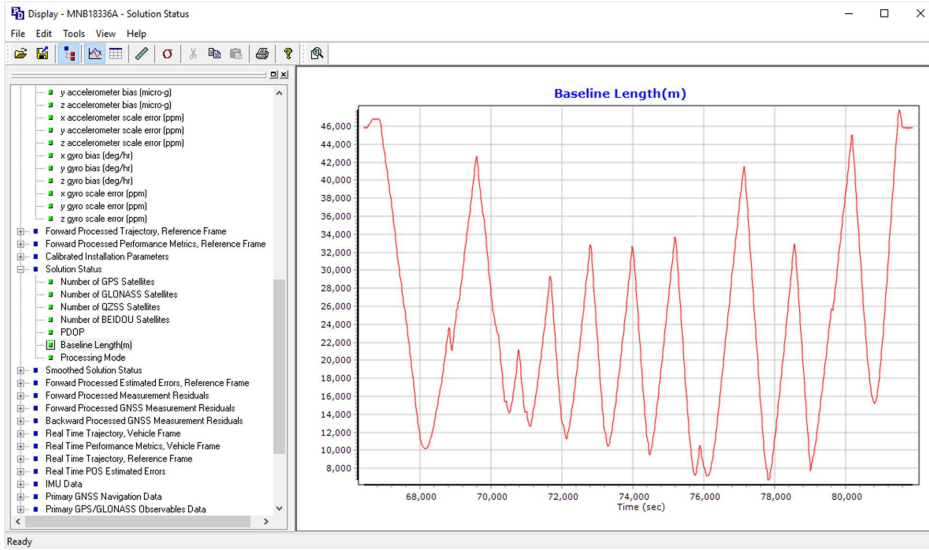
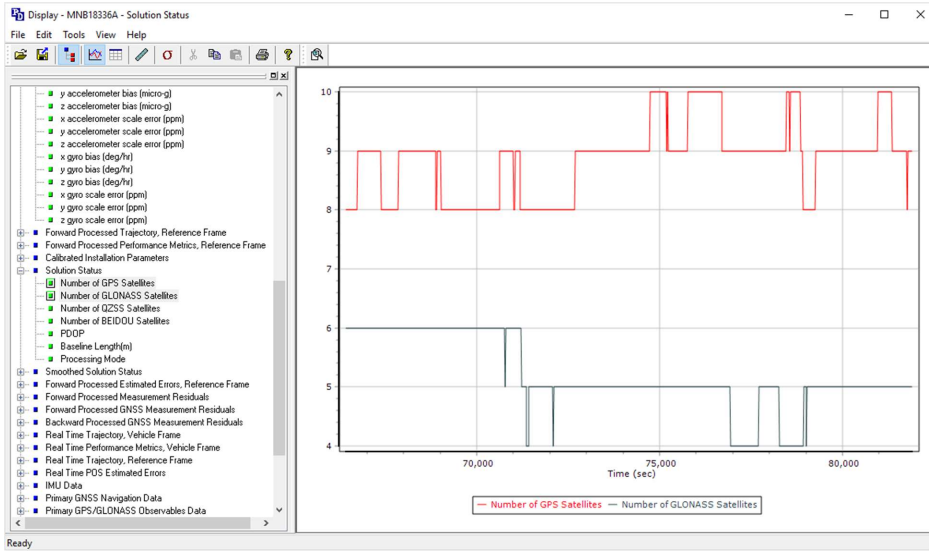
Seconds of start week Primary GNSS 1.000000

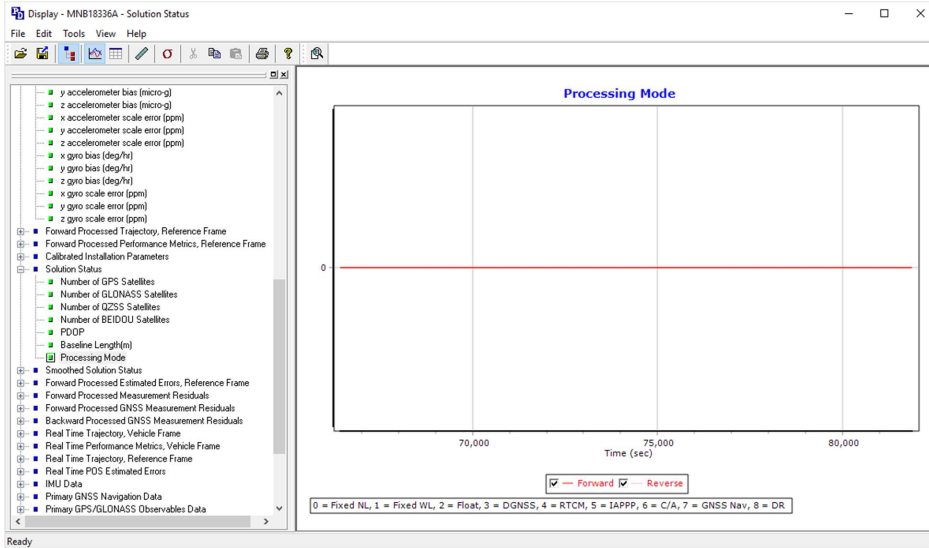
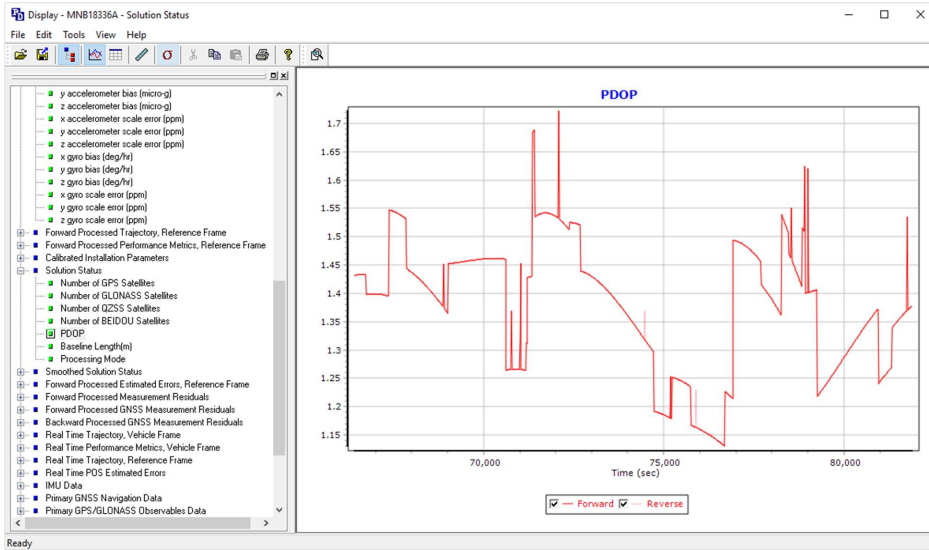
UTC Offset: 18.000

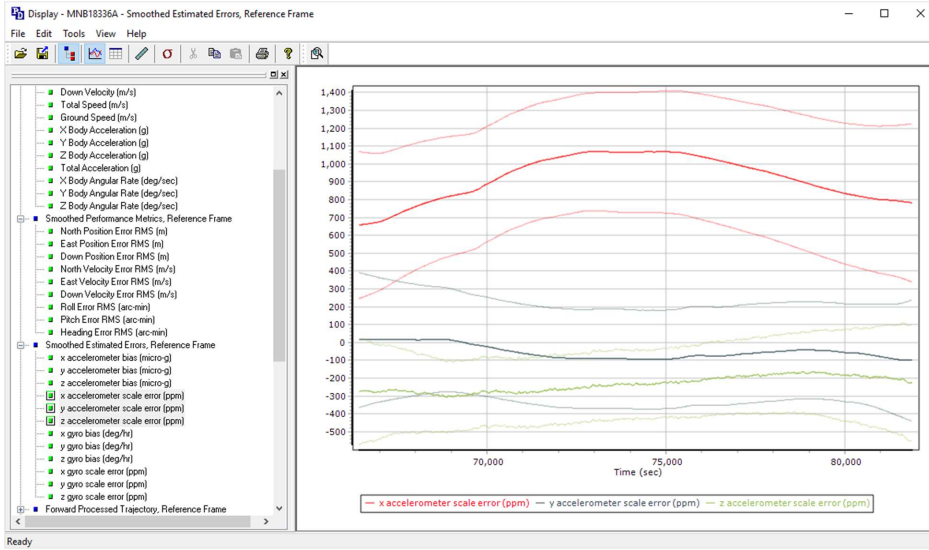
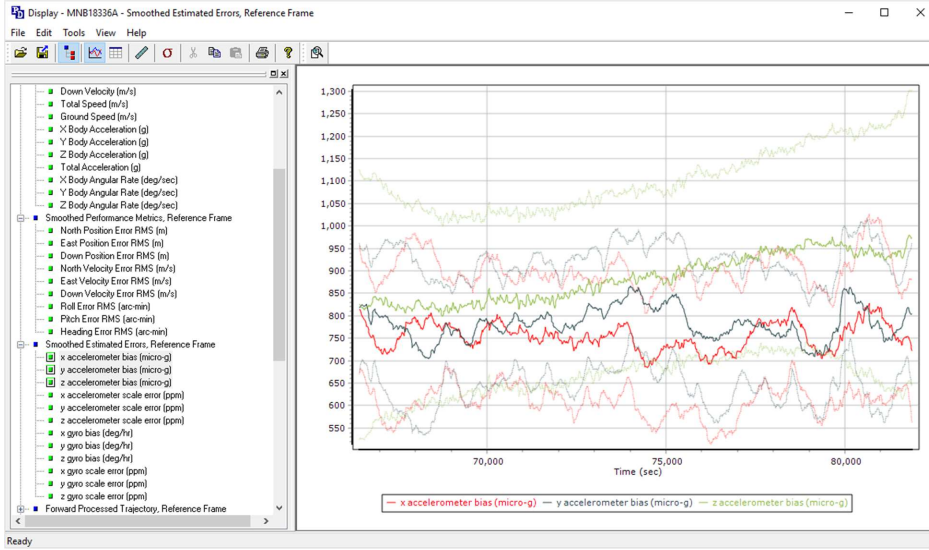


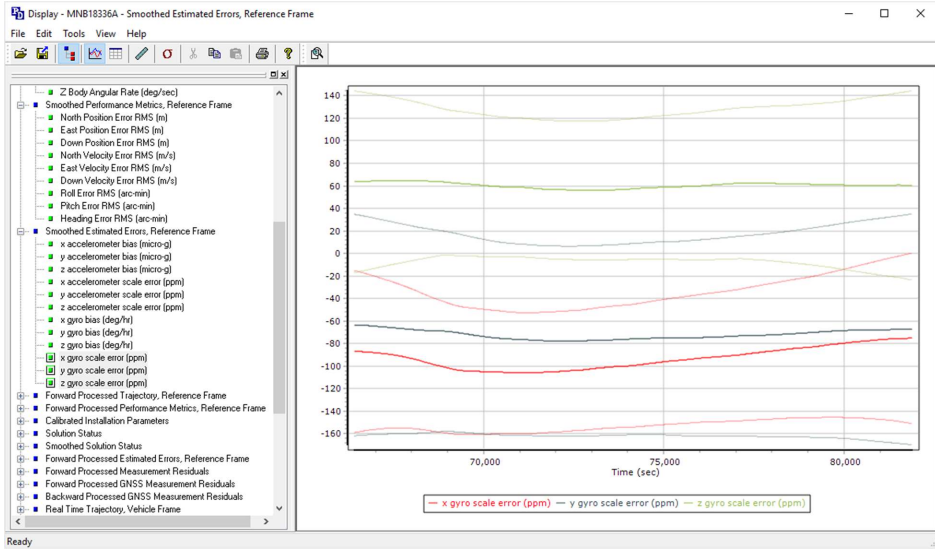
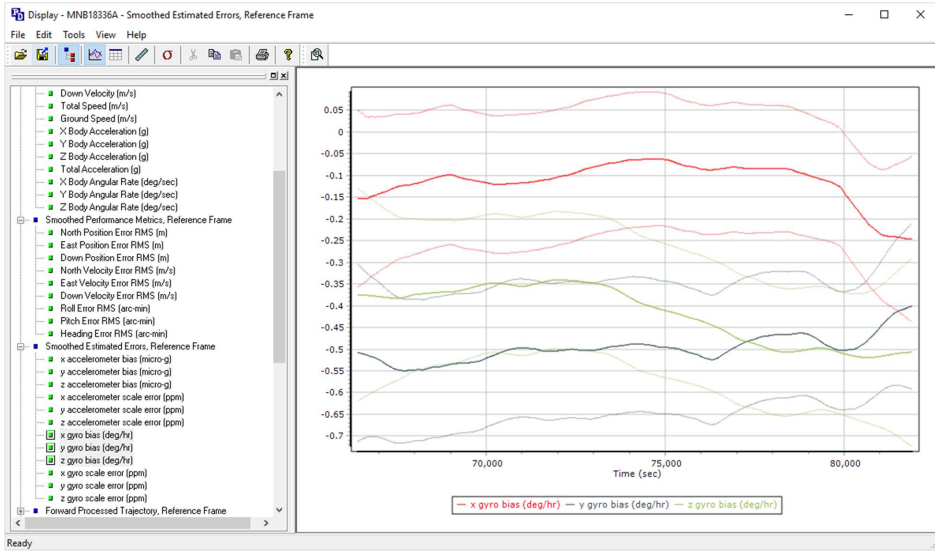




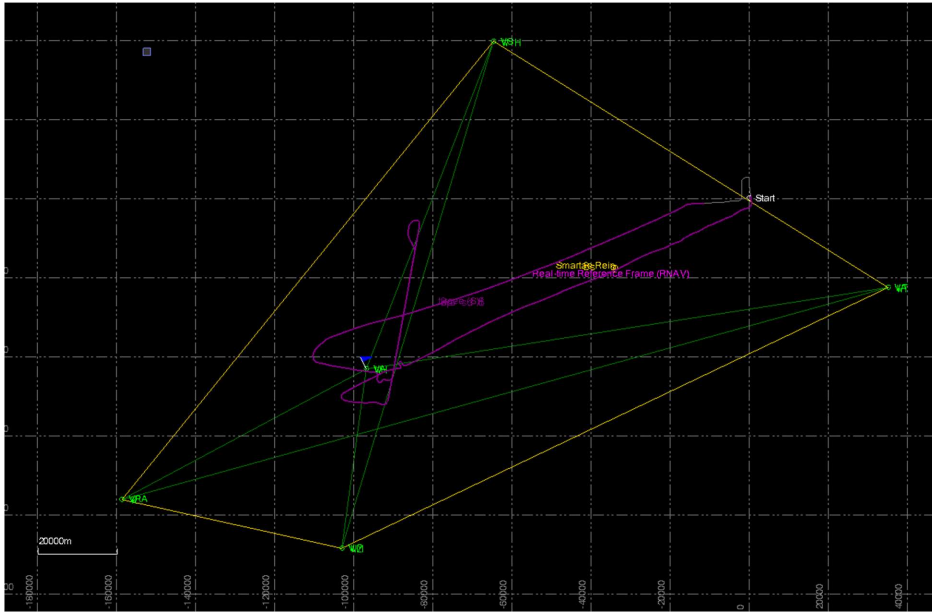








MNB19087A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
|----------------------------|----------------------------------|
| X: 0.034 m | X: 0.000 deg |
| Y: 0.018 m | Y: 0.000 deg |
| Z: -0.155 m | Z: 0.000 deg |

| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
|-------------------------------------|---------------------------------------|
| X: -0.150 m | X: 0.000 deg |
| Y: -0.061 m | Y: 0.000 deg |
| Z: -0.992 m | Z: 0.000 deg |

Standard Deviation: <3cm 10cm 50cm 1m 10m

Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
- Timing**
- Algorithms
- Initialization

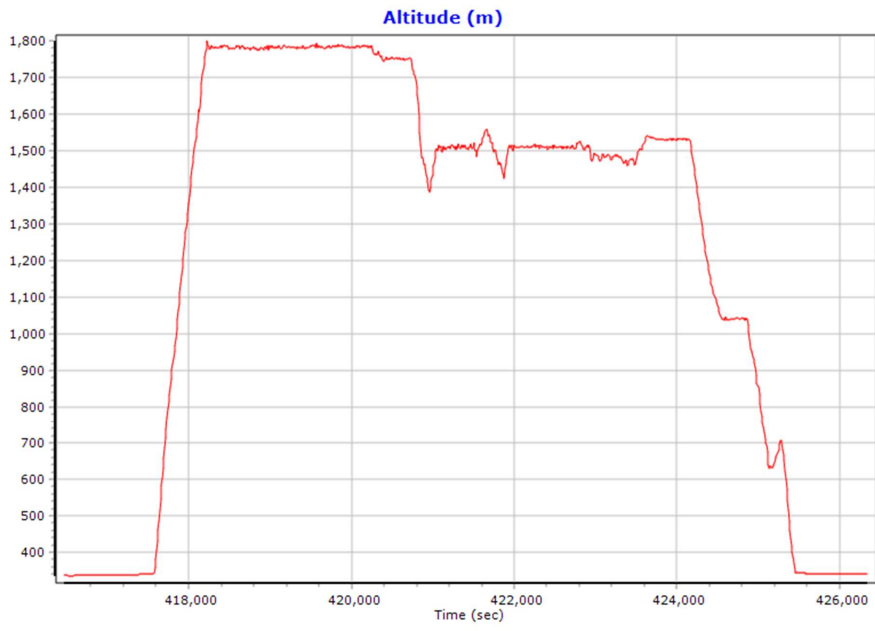
Timing

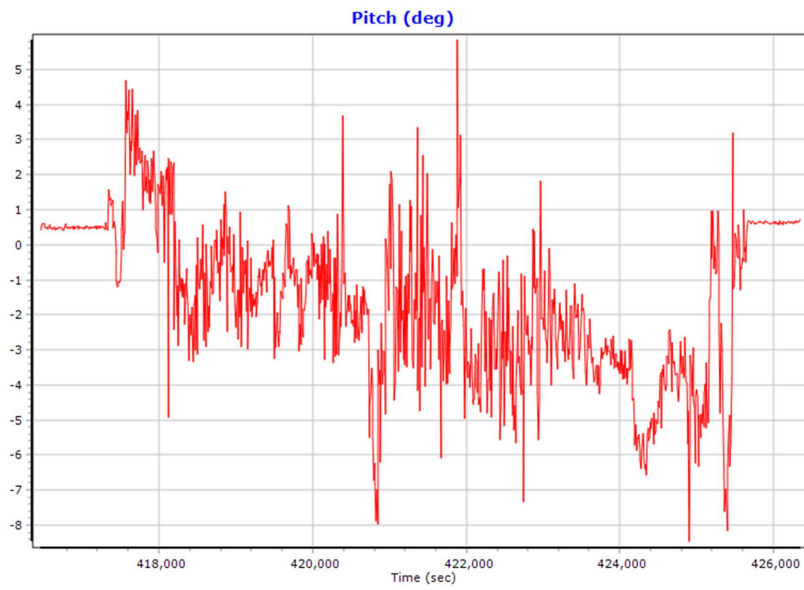
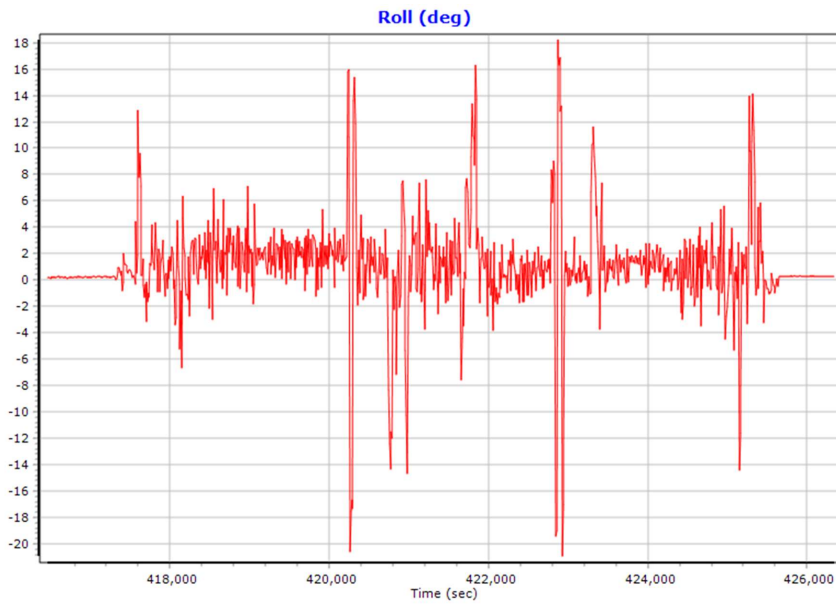
Start: 417000.000
End: 425000.000

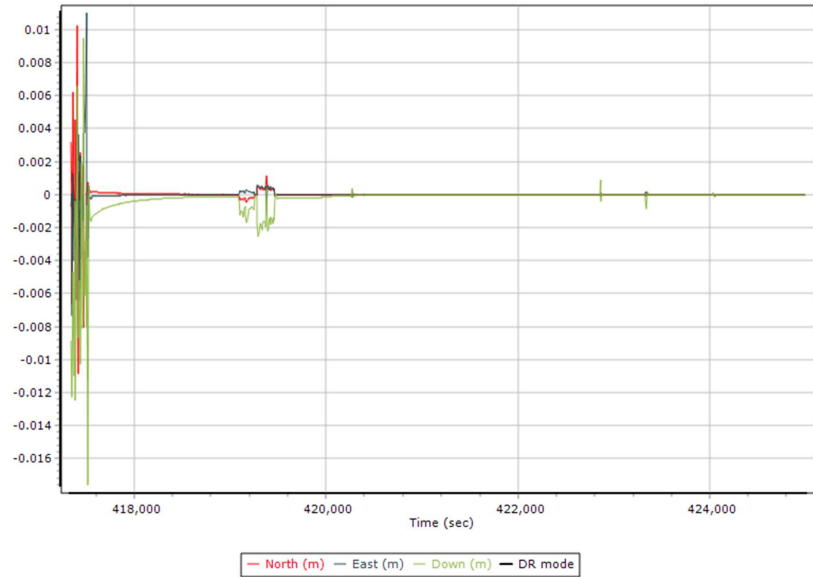
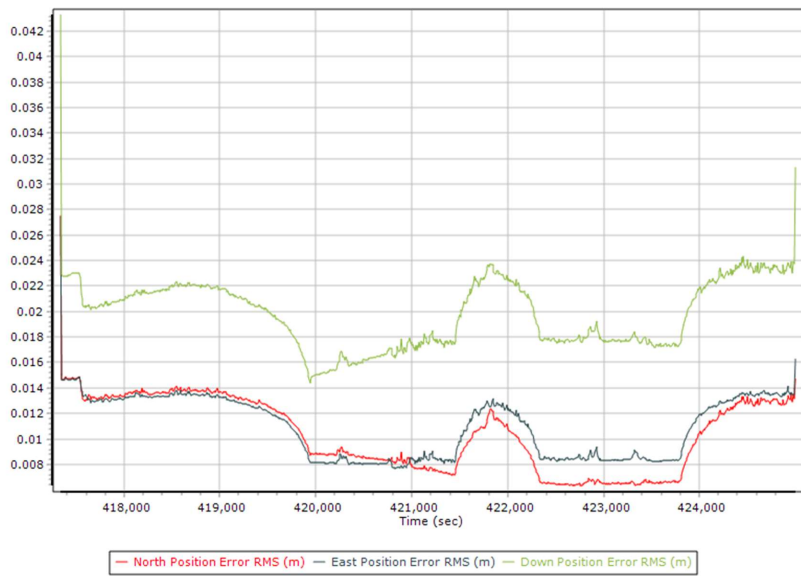
Entire time interval
 Seconds of start week

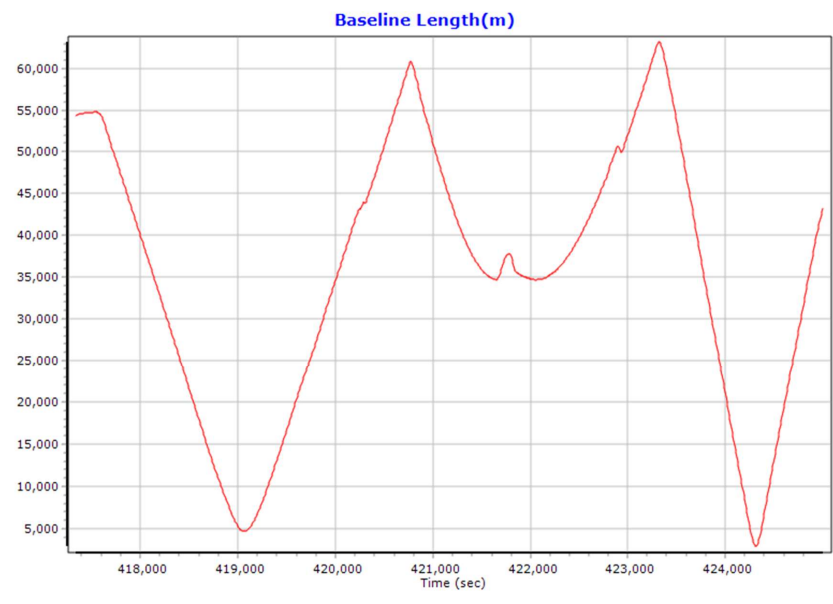
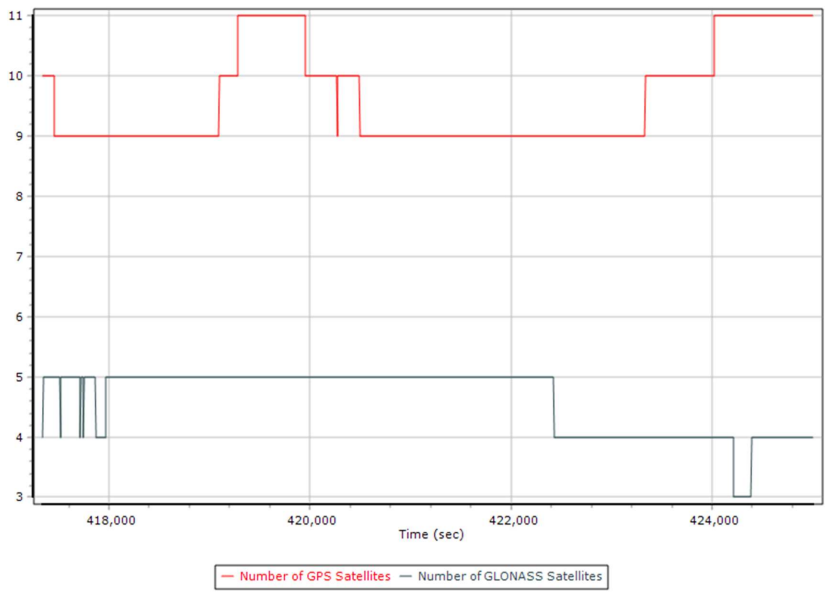
UTC Offset: 18.000

| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

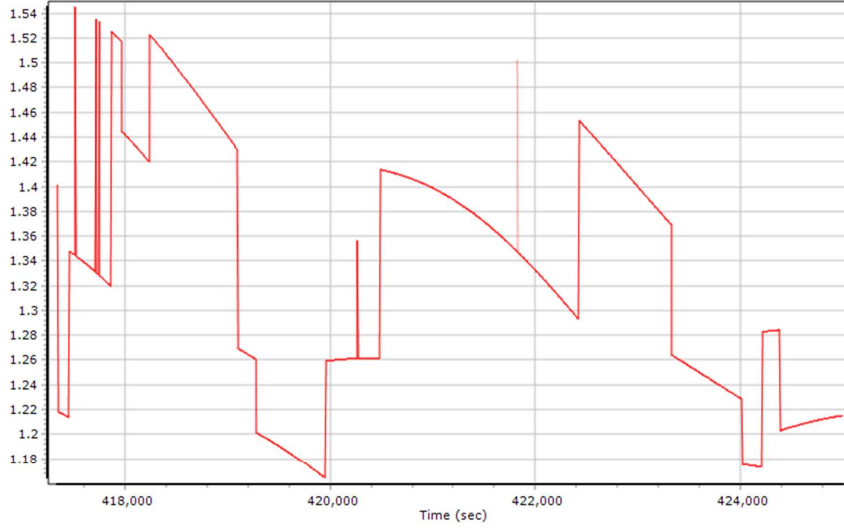






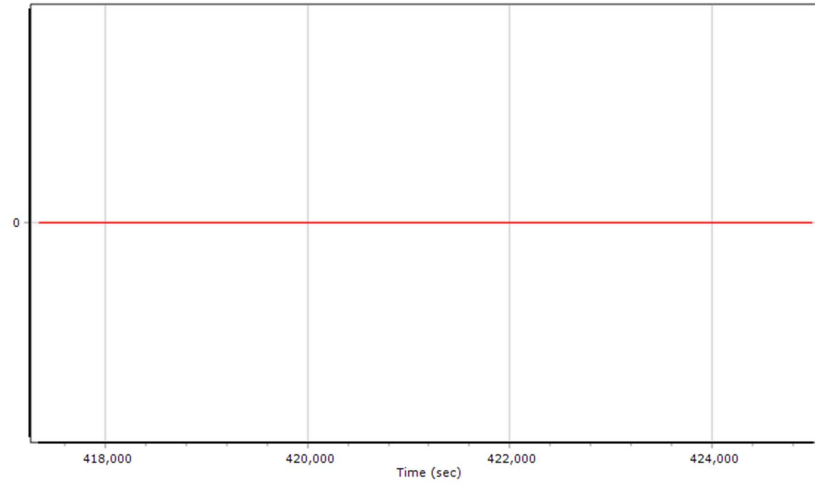


PDOP



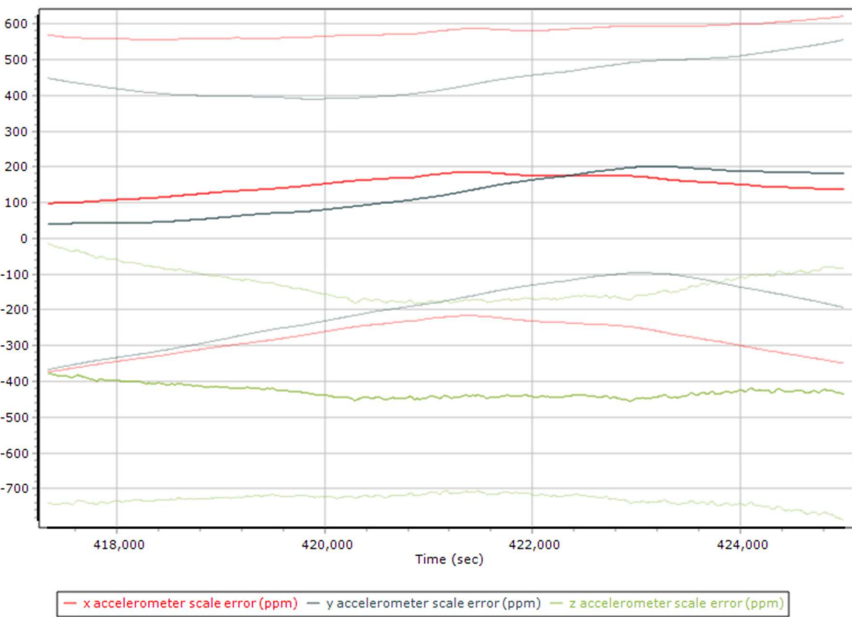
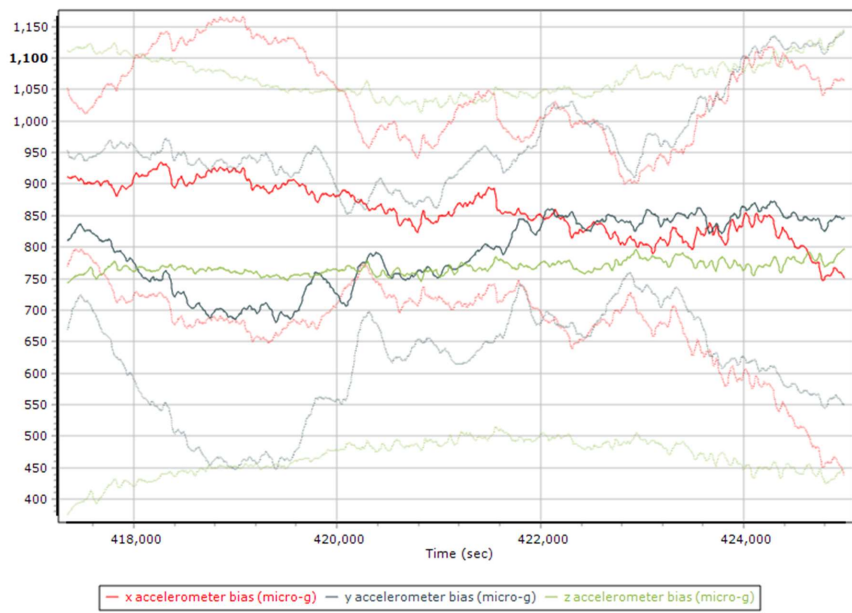
Forward Reverse

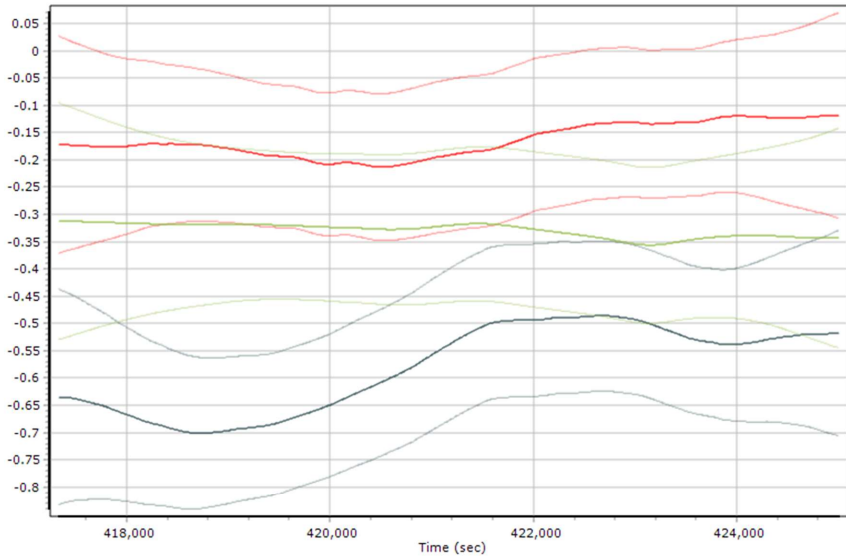
Processing Mode



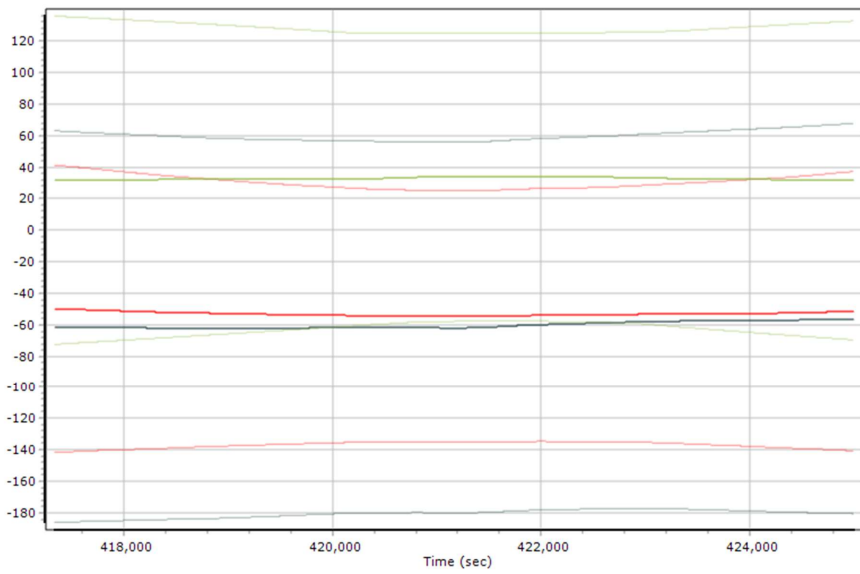
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



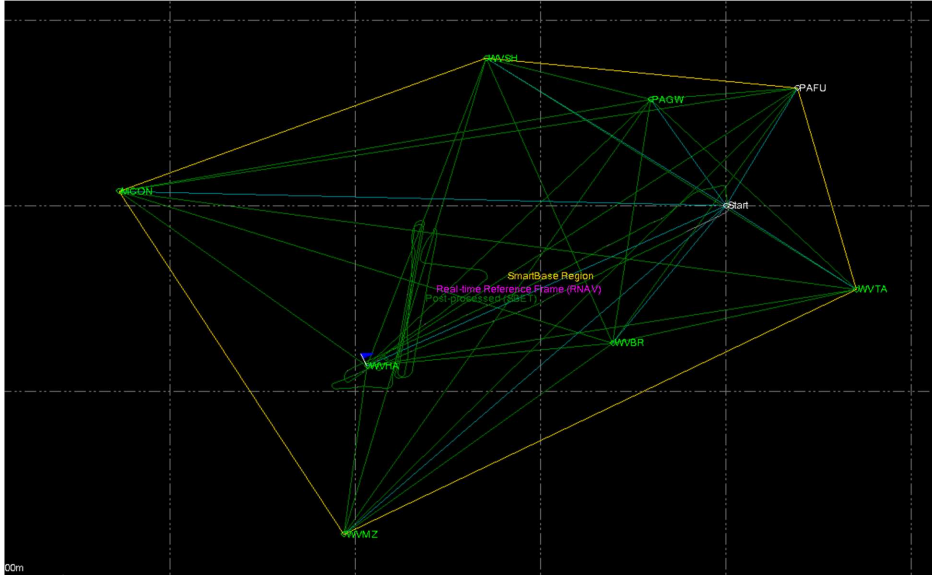


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



— x gyro scale error (ppm) — y gyro scale error (ppm) — z gyro scale error (ppm)

MNB19089A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
|----------------------------|----------------------------------|
| X: 0.034 m | X: 0.000 deg |
| Y: 0.018 m | Y: 0.000 deg |
| Z: -0.155 m | Z: 0.000 deg |

| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
|-------------------------------------|---------------------------------------|
| X: -0.150 m | X: 0.000 deg |
| Y: -0.061 m | Y: 0.000 deg |
| Z: -0.992 m | Z: 0.000 deg |

Standard Deviation: <3cm 10cm 50cm 1m 10m

OK Cancel

Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing**
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles

Timing

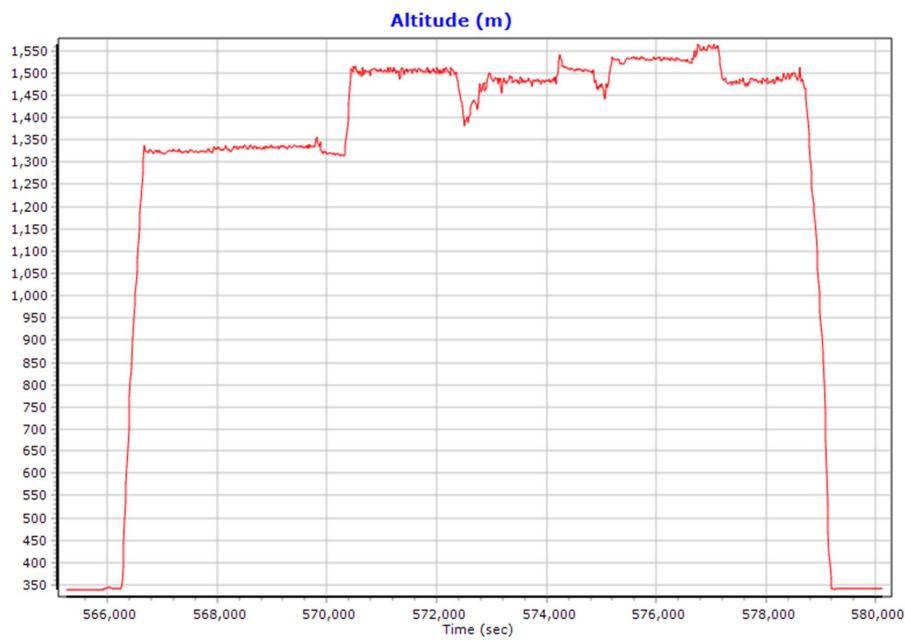
Start: 566700.000 Data Incr. (sec)

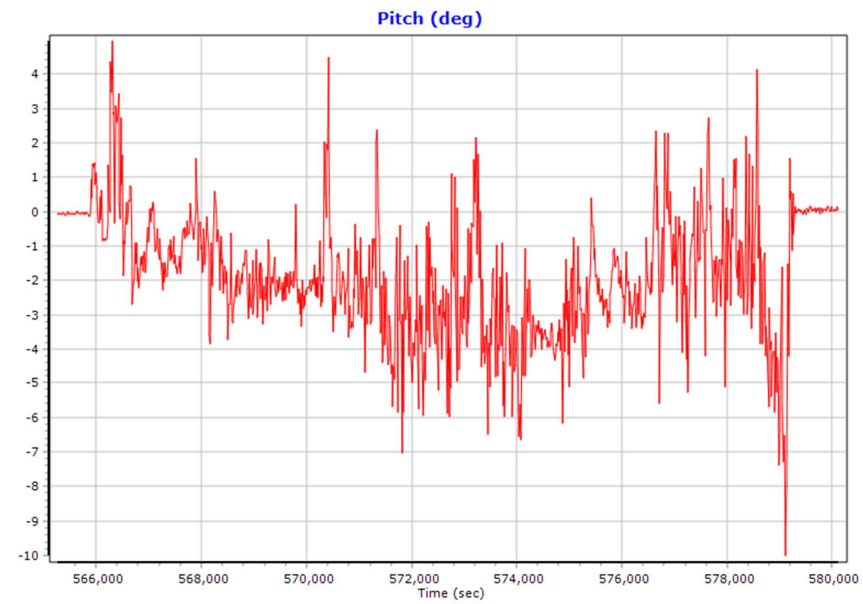
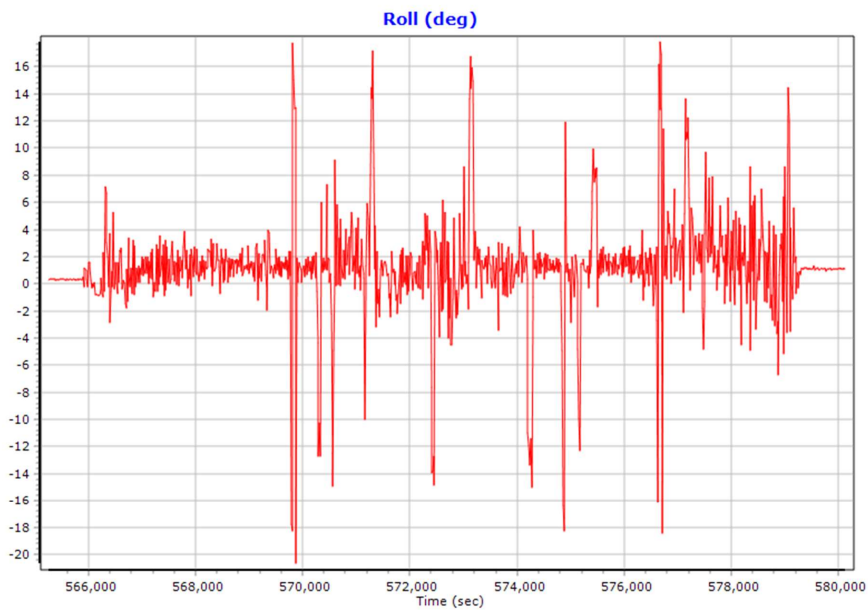
End: 580127.000 Output Record 0.005000

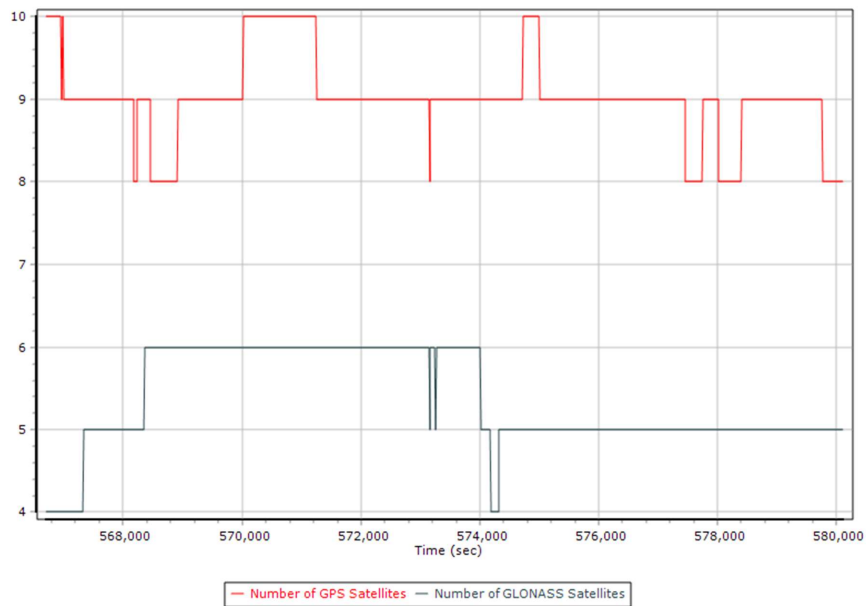
Entire time interval IMU 0.005000

Seconds of start week Primary GNSS 1.000000

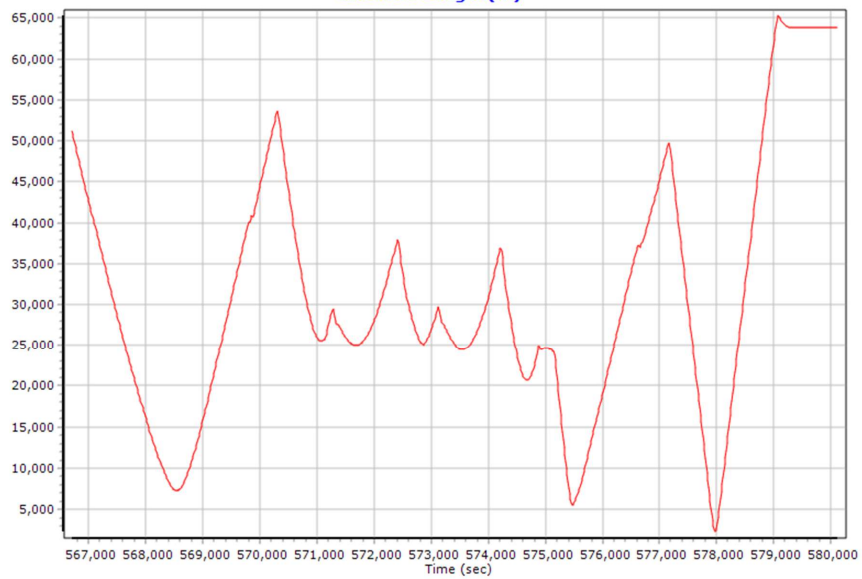
UTC Offset: 18.000

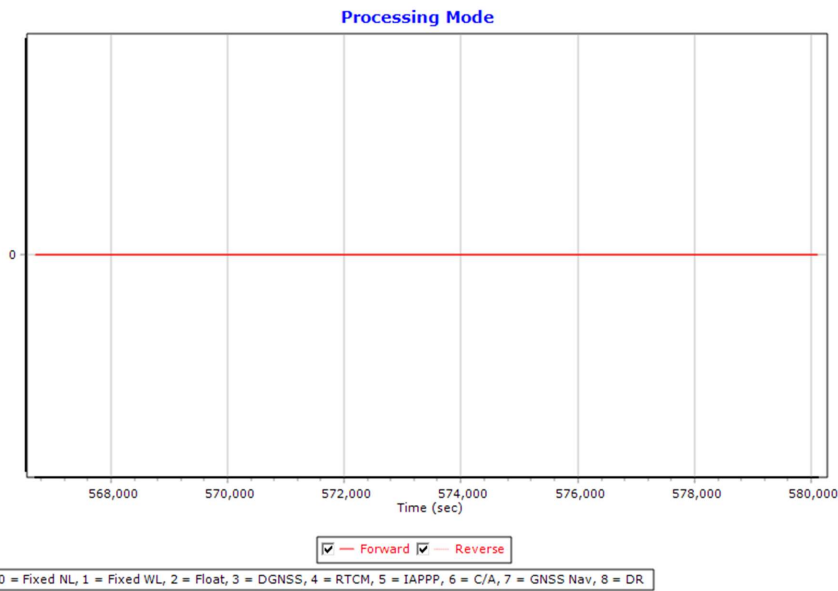
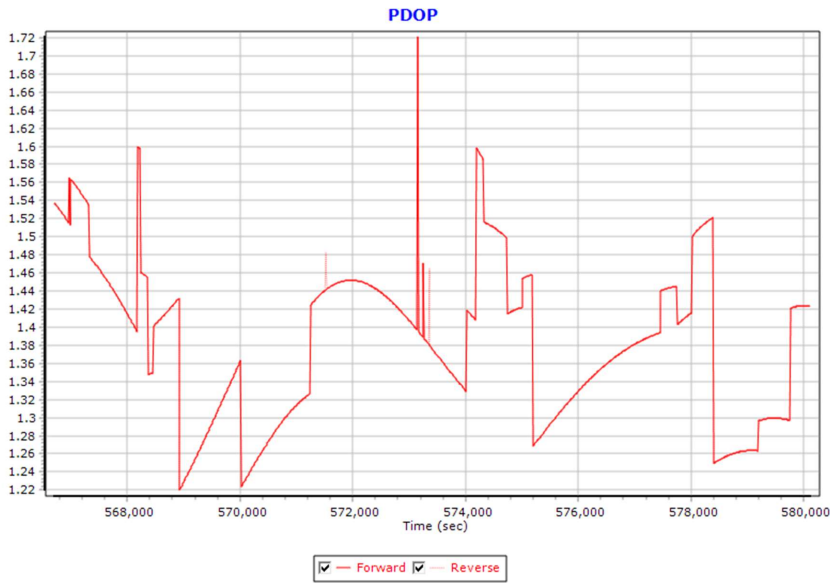


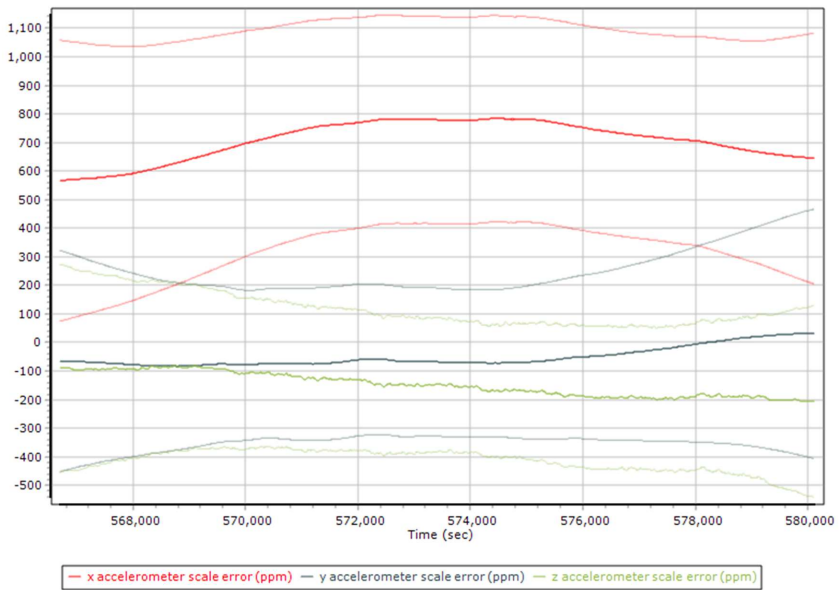
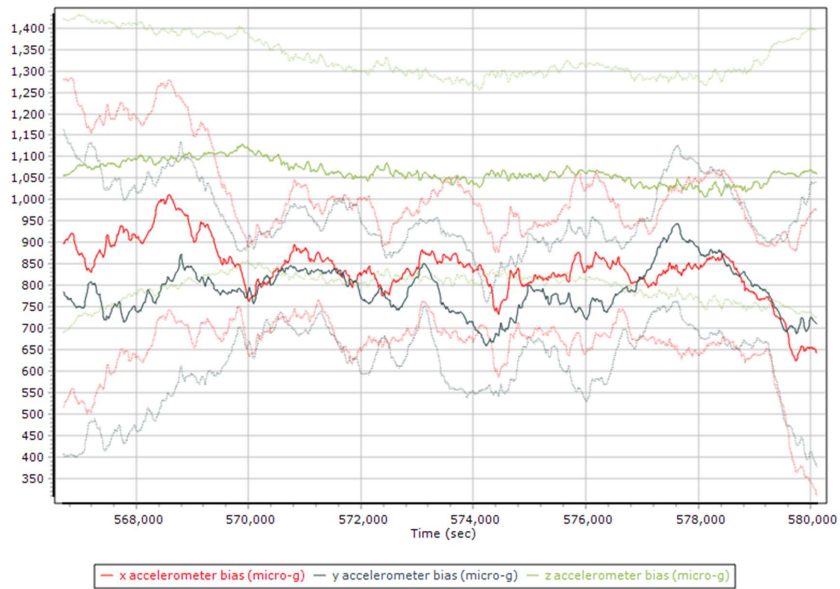


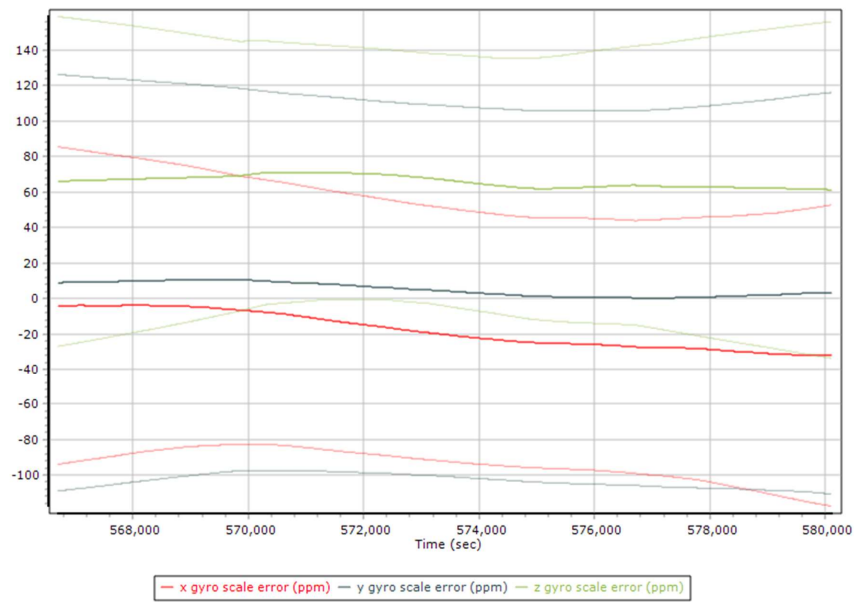
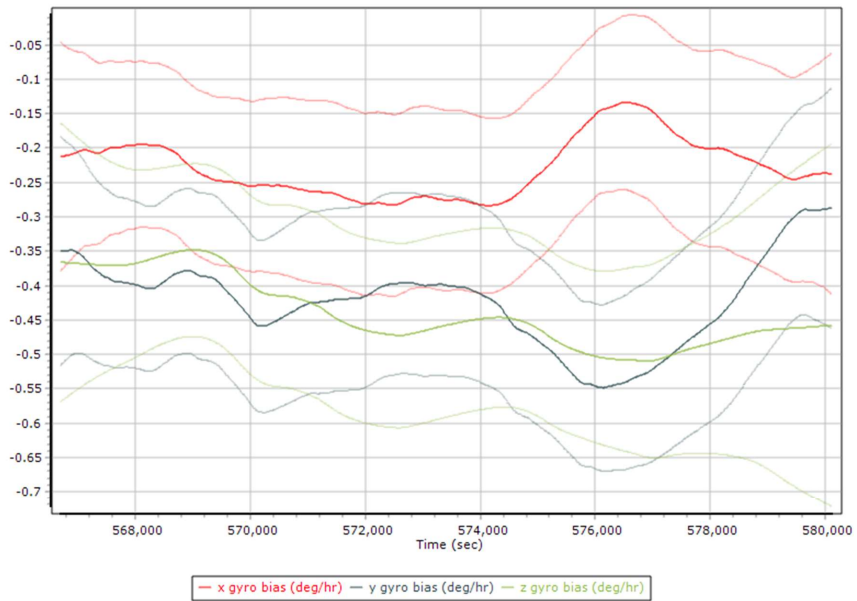


Baseline Length(m)

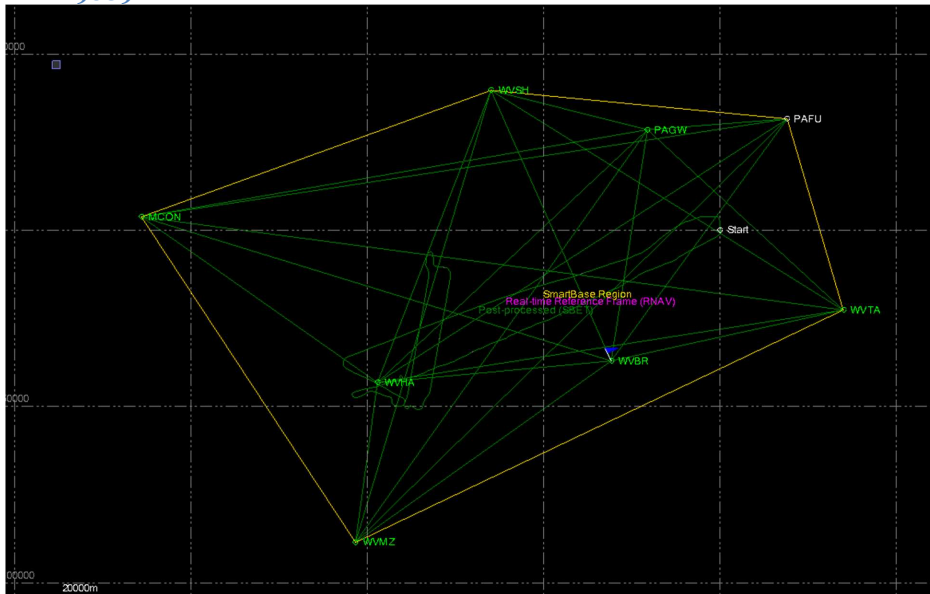








MNB19089B



Project Settings

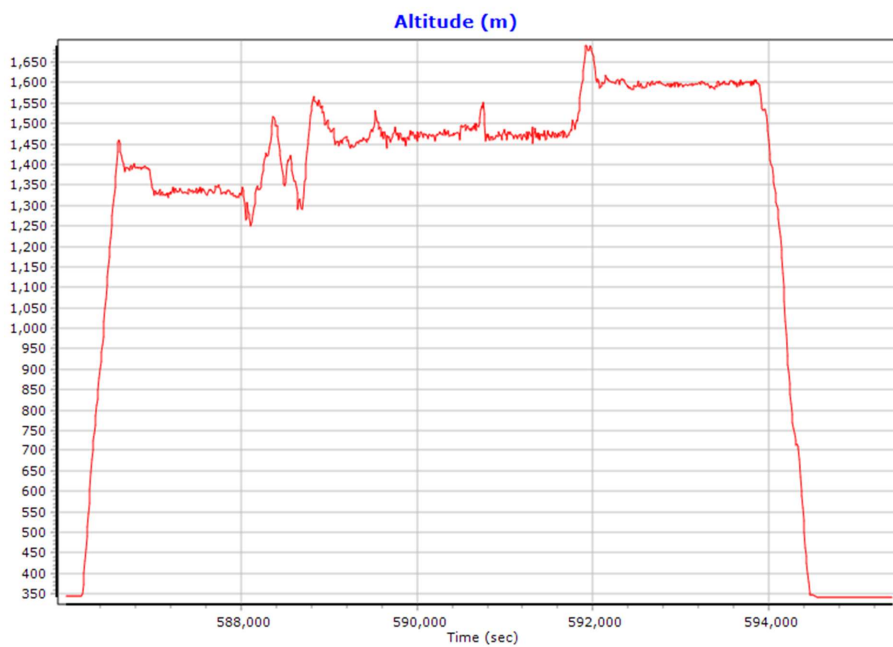
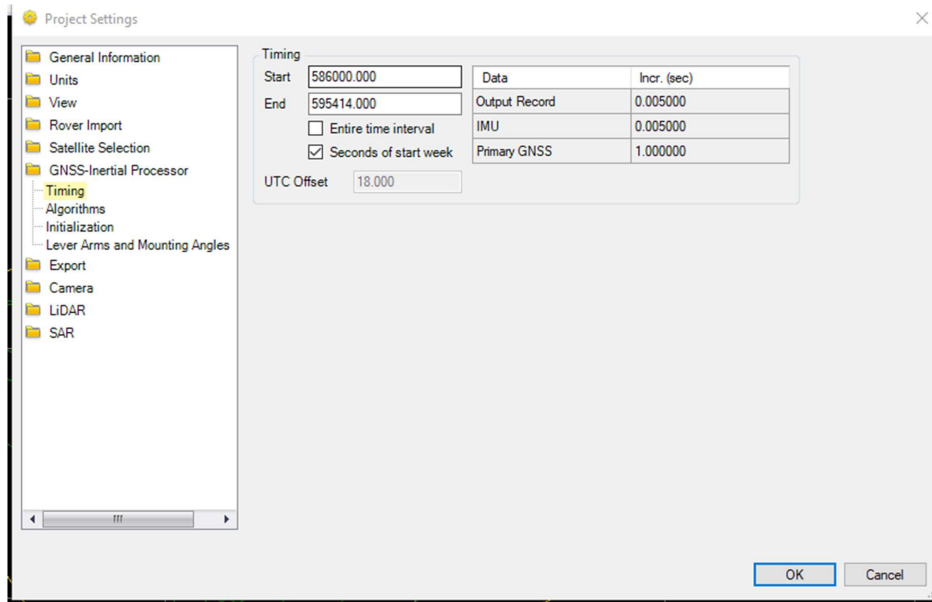
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

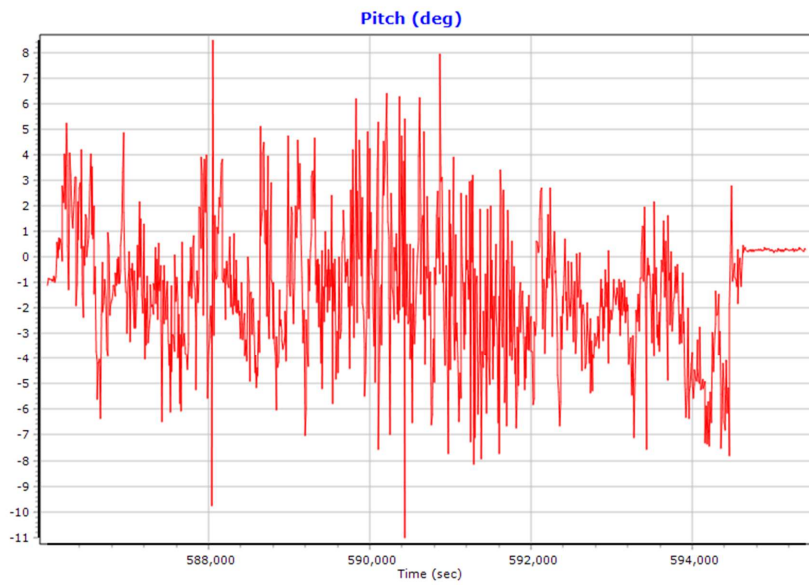
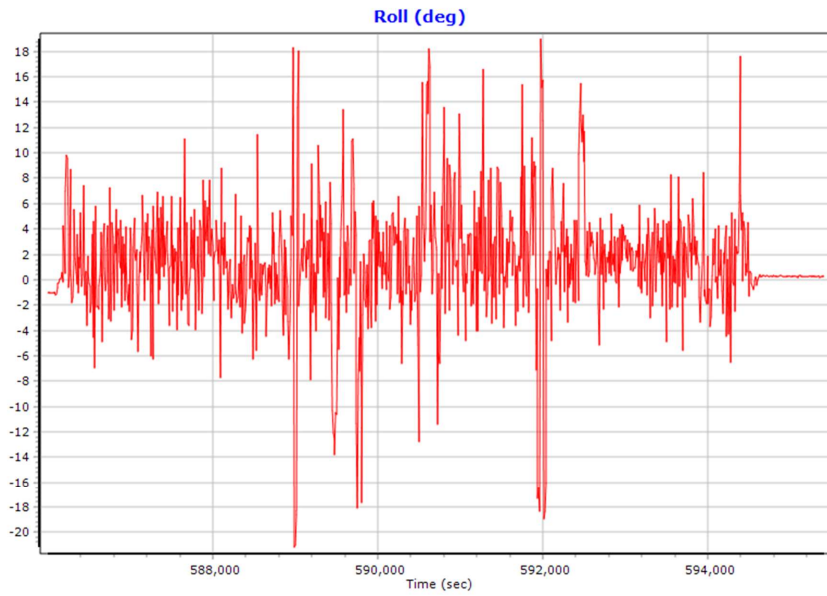
| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
|----------------------------|----------------------------------|
| X: 0.034 m | X: 0.000 deg |
| Y: 0.018 m | Y: 0.000 deg |
| Z: -0.155 m | Z: 0.000 deg |

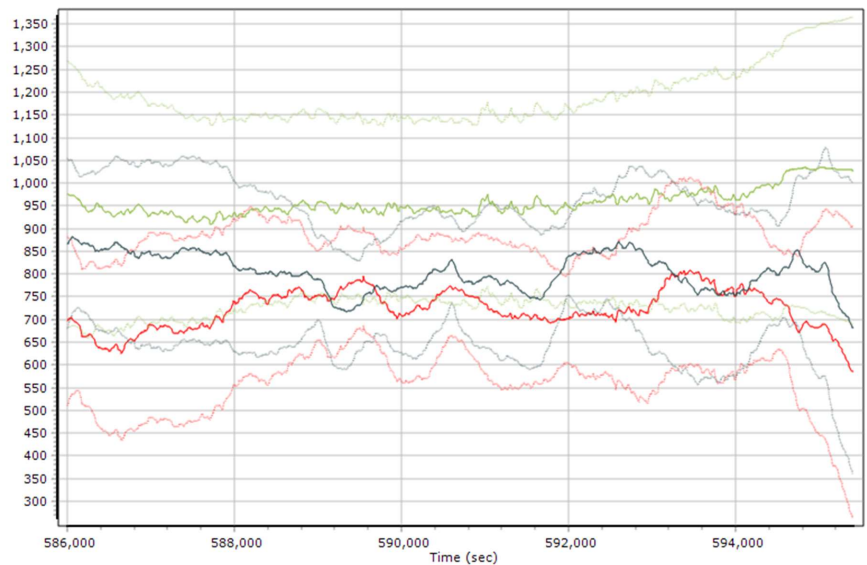
| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
|-------------------------------------|---------------------------------------|
| X: -0.150 m | X: 0.000 deg |
| Y: -0.061 m | Y: 0.000 deg |
| Z: -0.992 m | Z: 0.000 deg |

Standard Deviation: <3cm 10cm 50cm 1m 10m

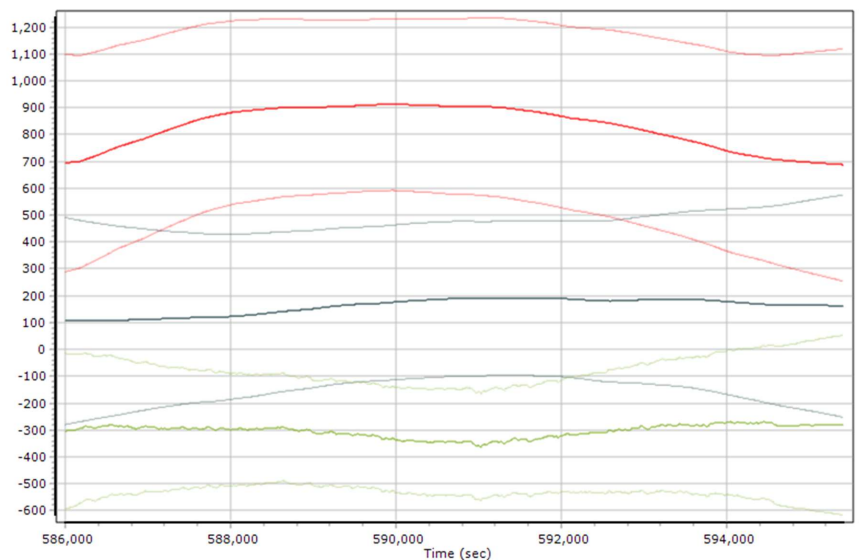
OK Cancel



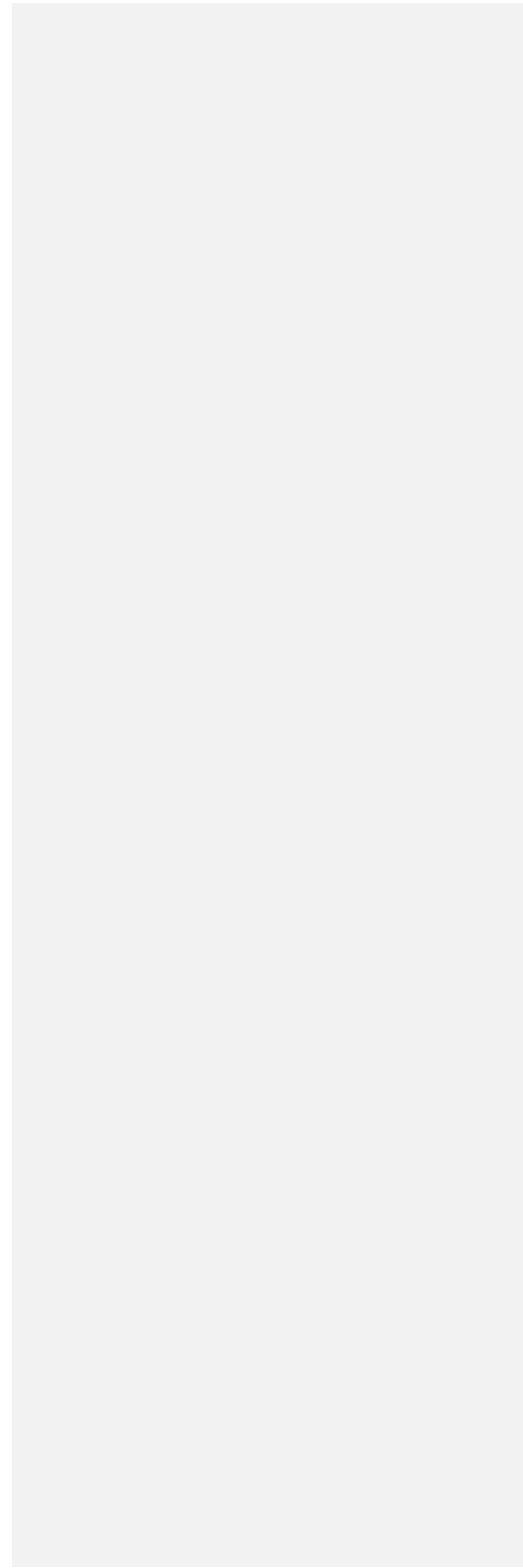
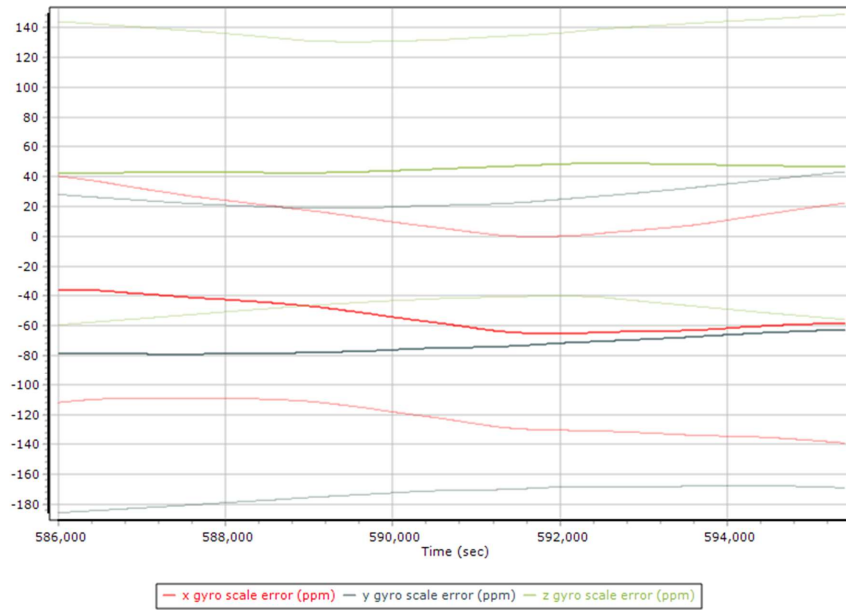
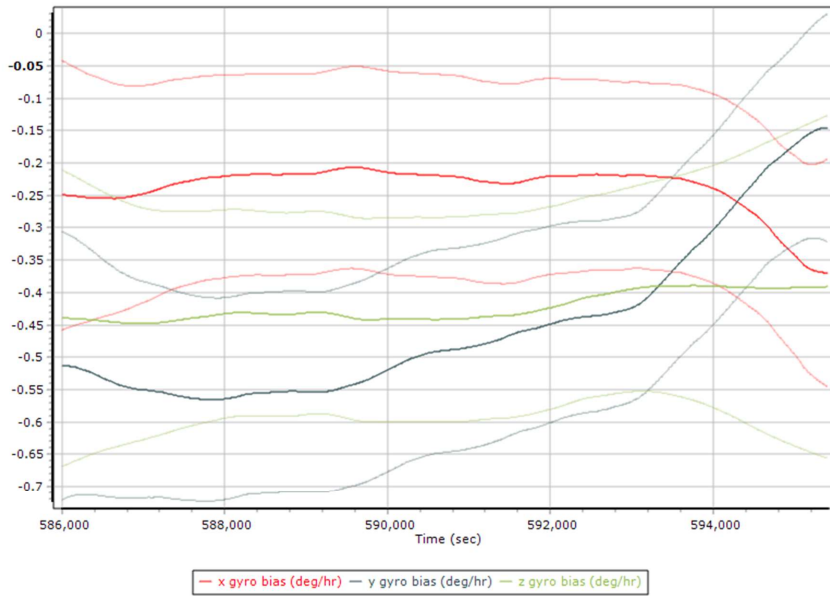




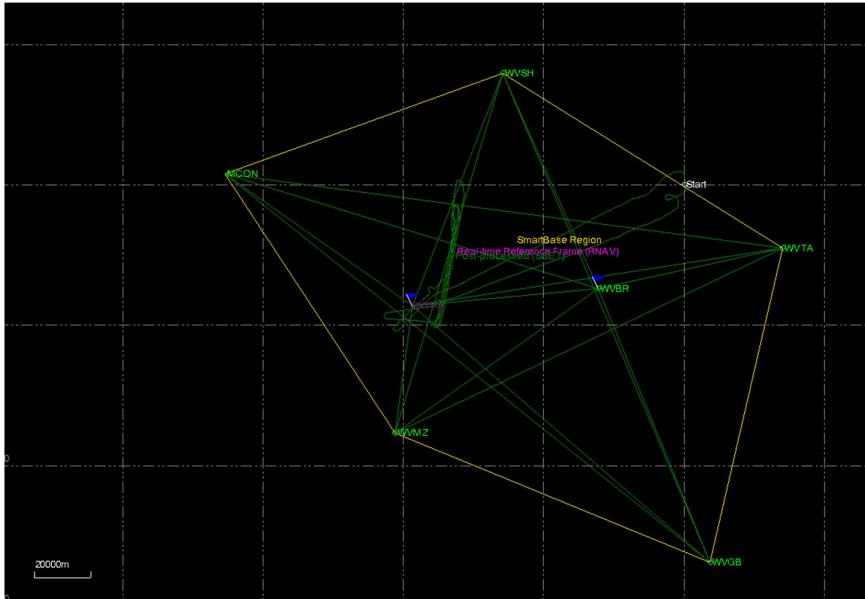
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



MNB19091A



Project Settings

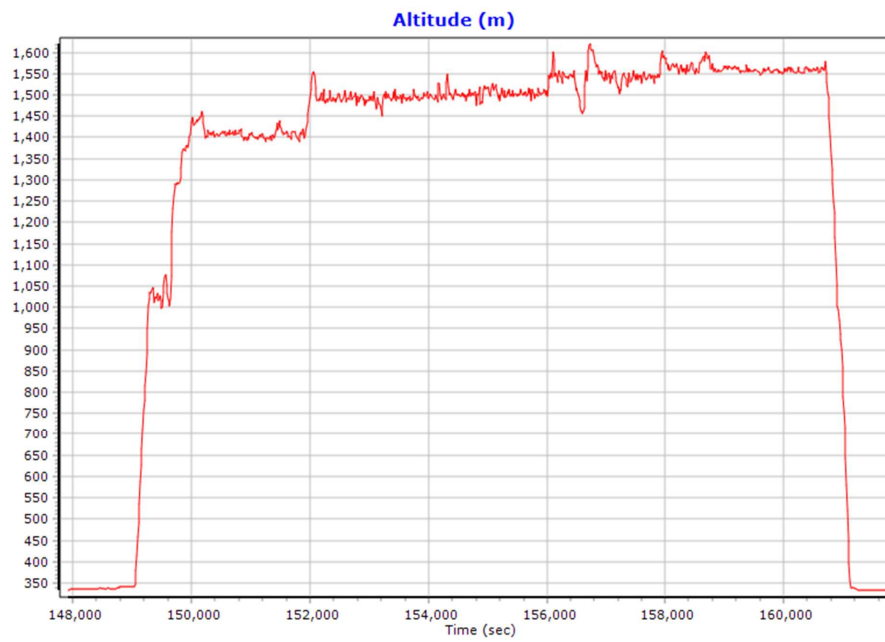
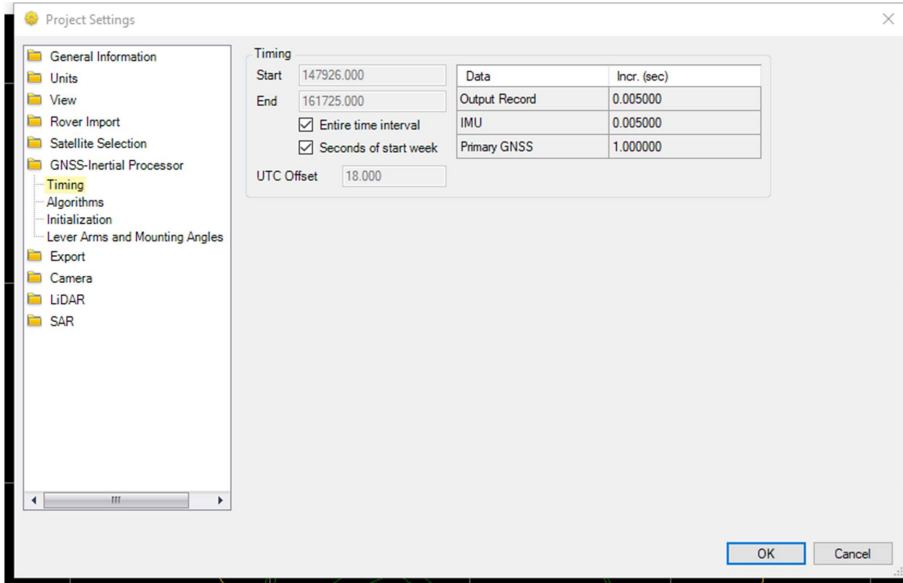
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

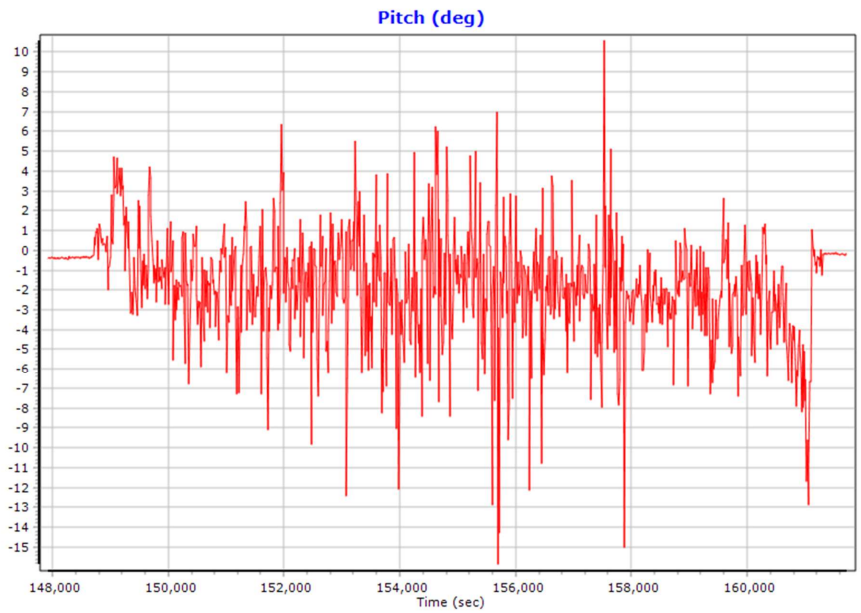
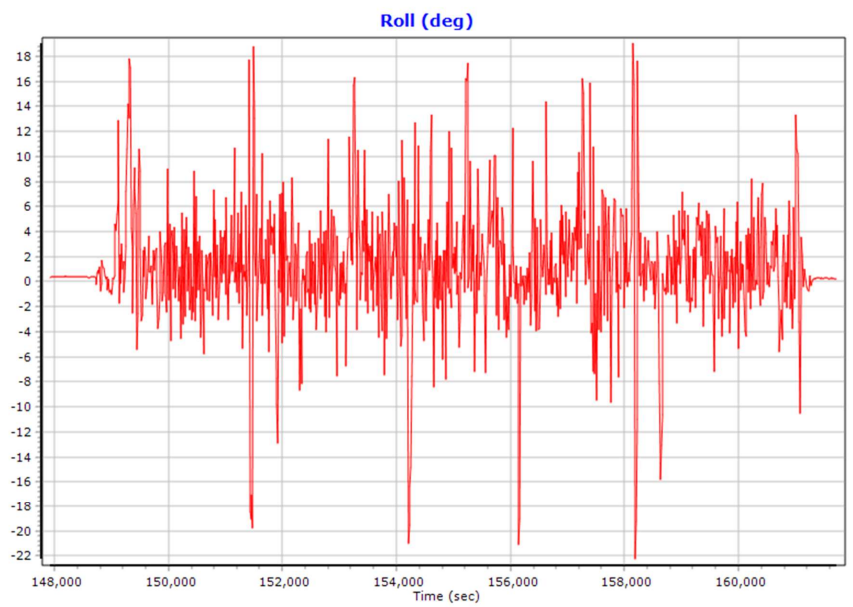
| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
|----------------------------|----------------------------------|
| X: 0.034 m | X: 0.000 deg |
| Y: 0.018 m | Y: 0.000 deg |
| Z: -0.155 m | Z: 0.000 deg |

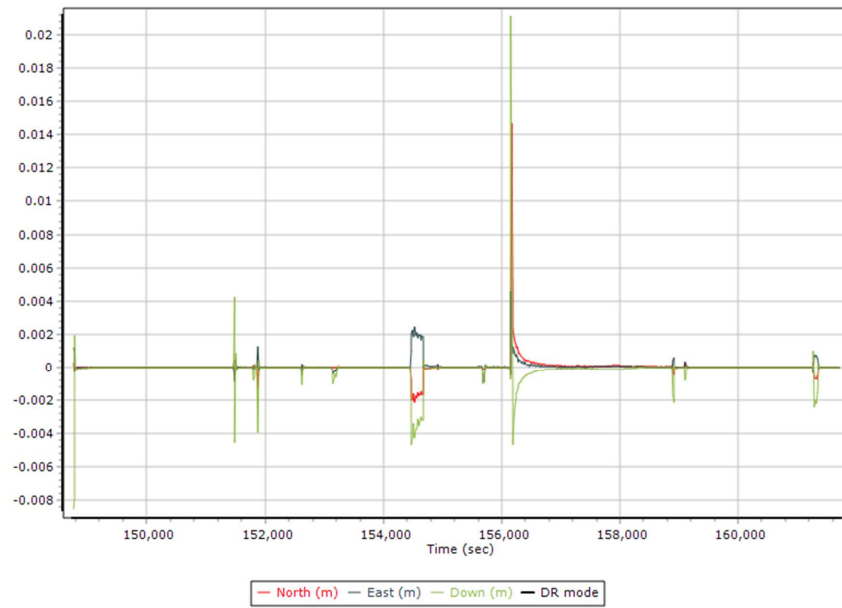
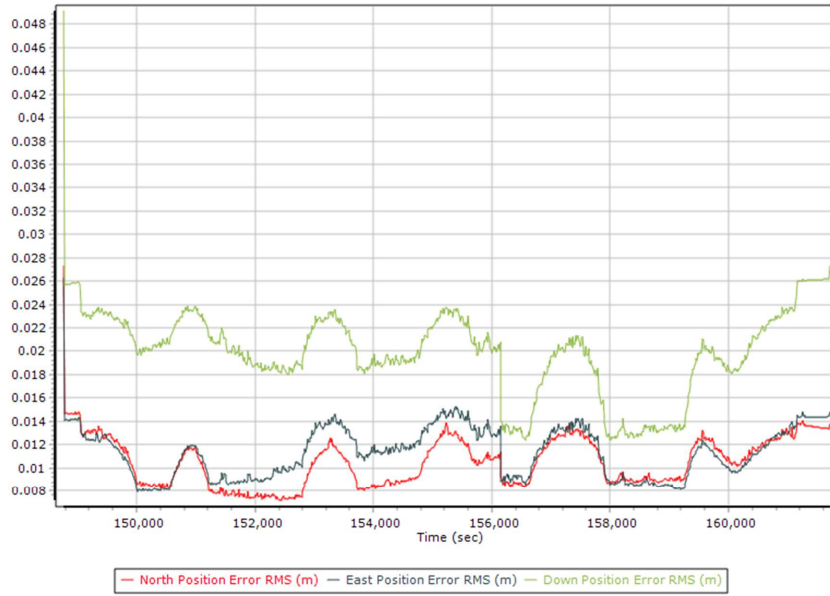
| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
|-------------------------------------|---------------------------------------|
| X: -0.150 m | X: 0.000 deg |
| Y: -0.061 m | Y: 0.000 deg |
| Z: -0.992 m | Z: 0.000 deg |

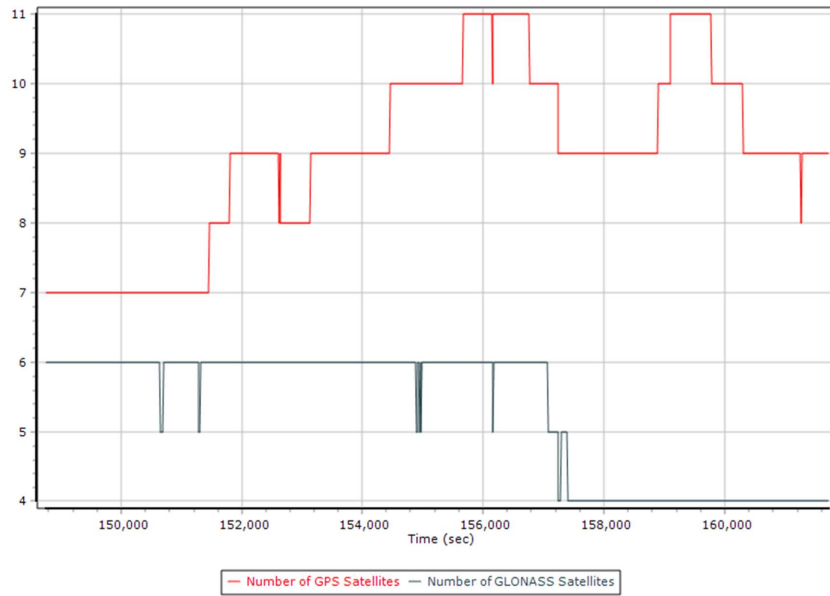
Standard Deviation: <3cm 10cm 50cm 1m 10m

OK Cancel

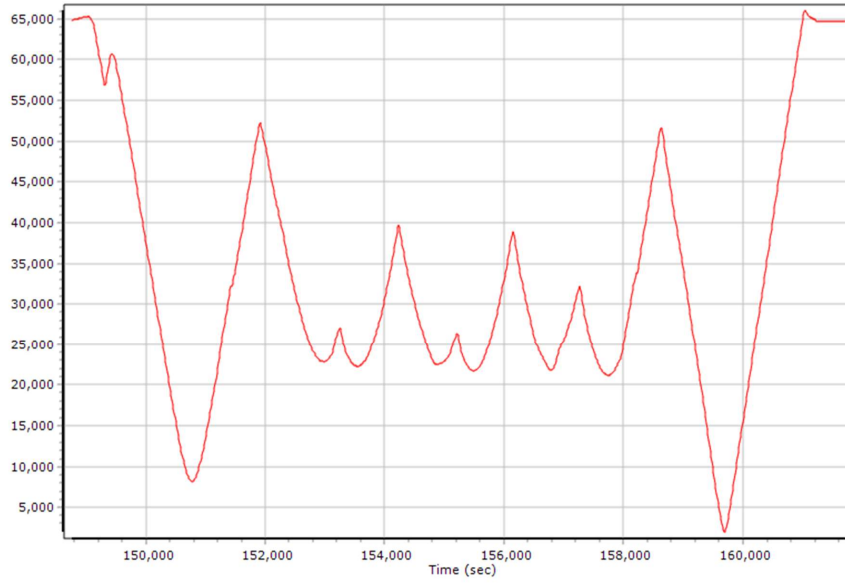








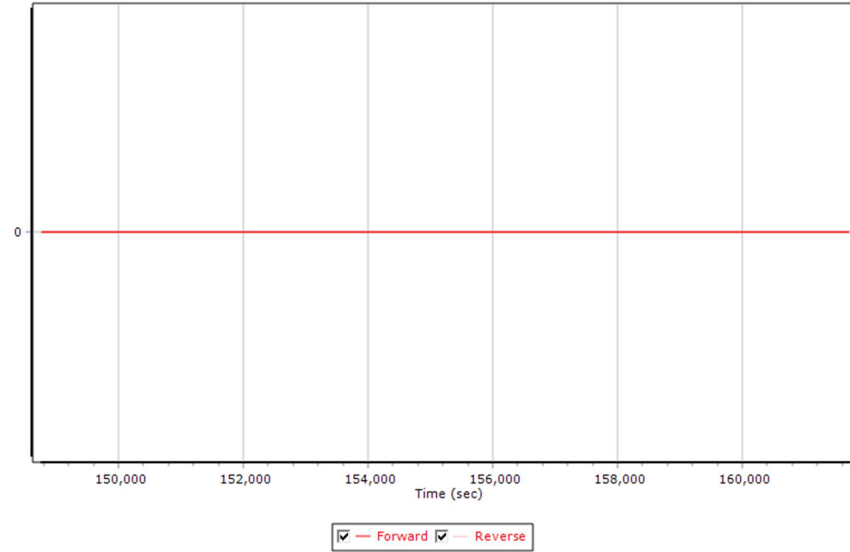
Baseline Length(m)



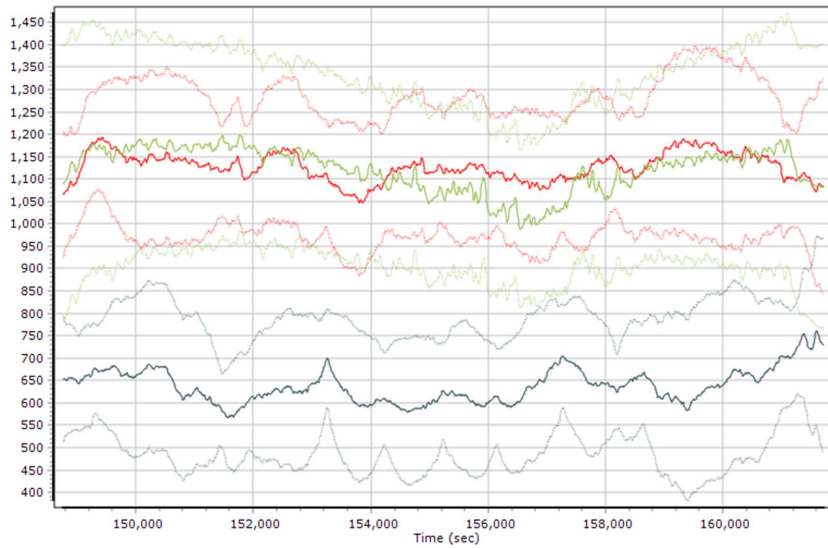
PDOP



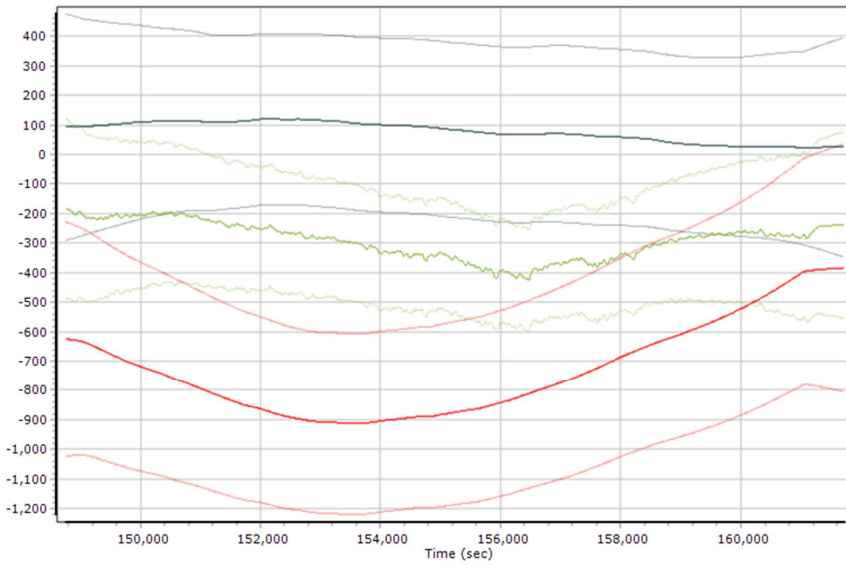
Processing Mode



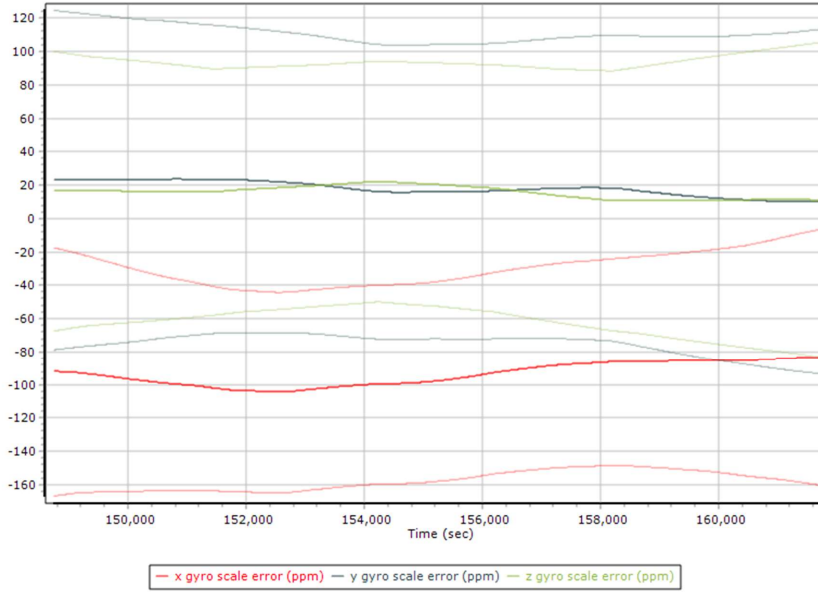
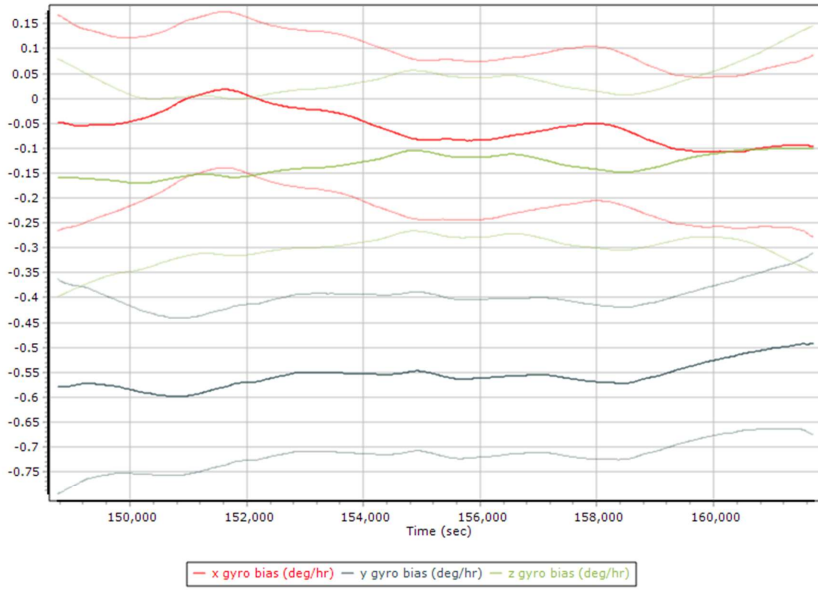
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



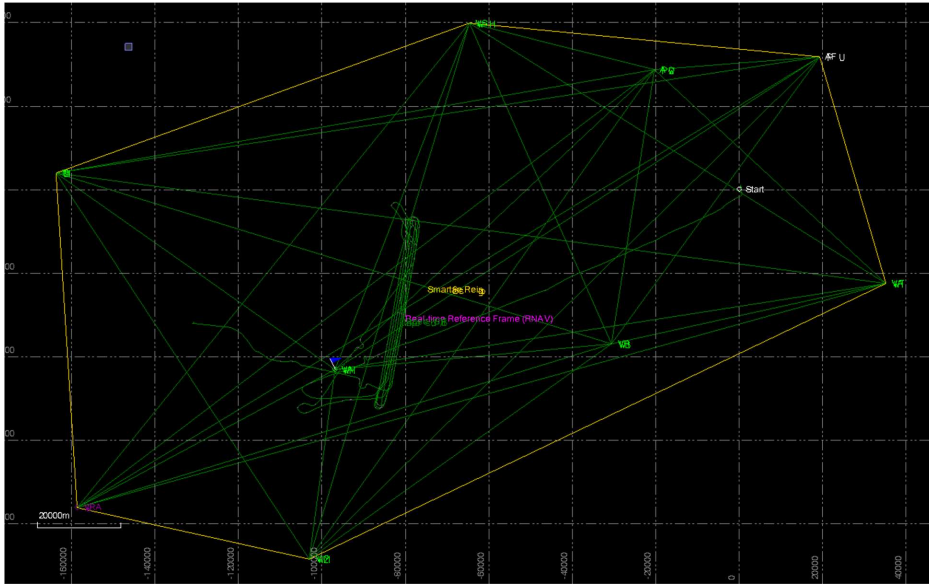
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



MNB19093A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
|----------------------------|----------------------------------|
| X: 0.034 m | X: 0.000 deg |
| Y: 0.018 m | Y: 0.000 deg |
| Z: -0.155 m | Z: 0.000 deg |

| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
|-------------------------------------|---------------------------------------|
| X: -0.150 m | X: 0.000 deg |
| Y: -0.061 m | Y: 0.000 deg |
| Z: -0.992 m | Z: 0.000 deg |

Standard Deviation: <3cm 10cm 50cm 1m 10m

OK Cancel

Project Settings

General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
Timing
Algorithms
Initialization
Lever Arms and Mounting Angles
Export
Camera
LiDAR
SAR

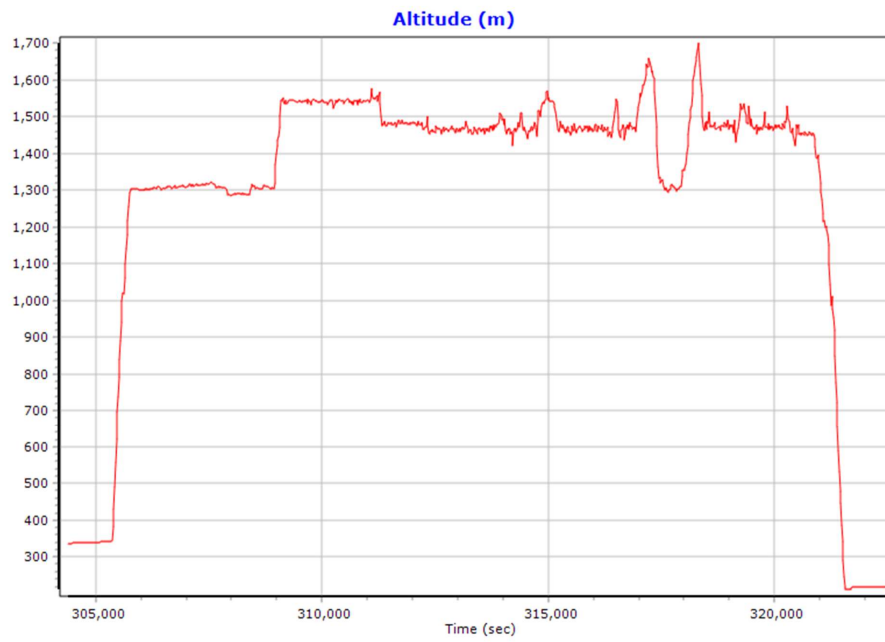
Timing

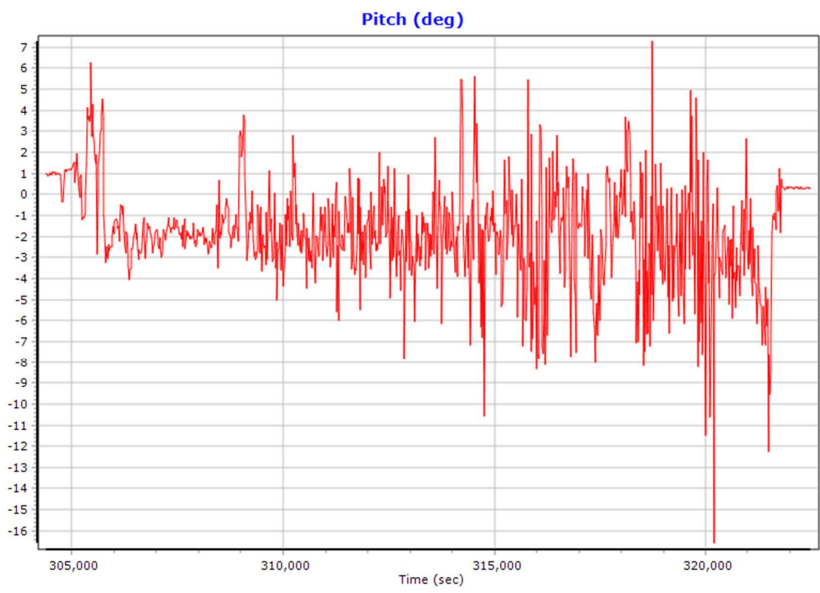
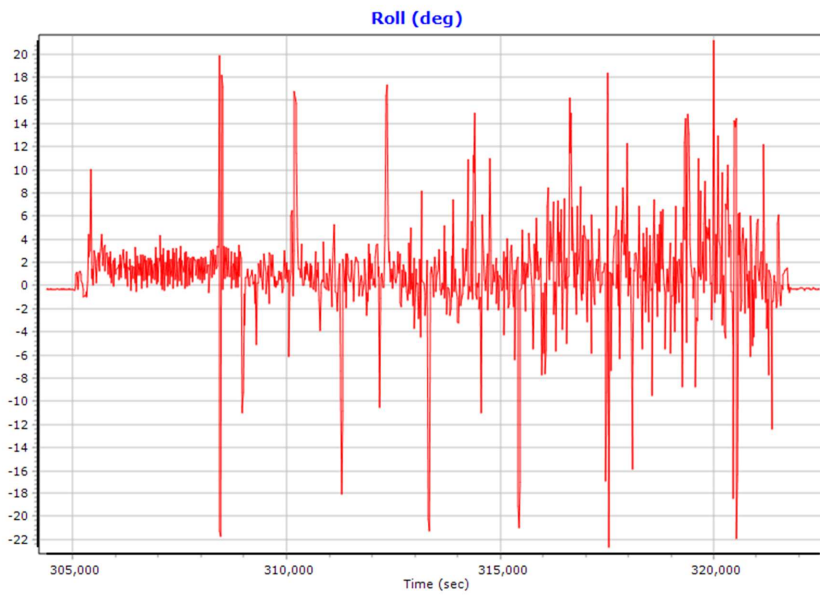
Start: 304386.000
End: 322480.000
UTC Offset: 18.000

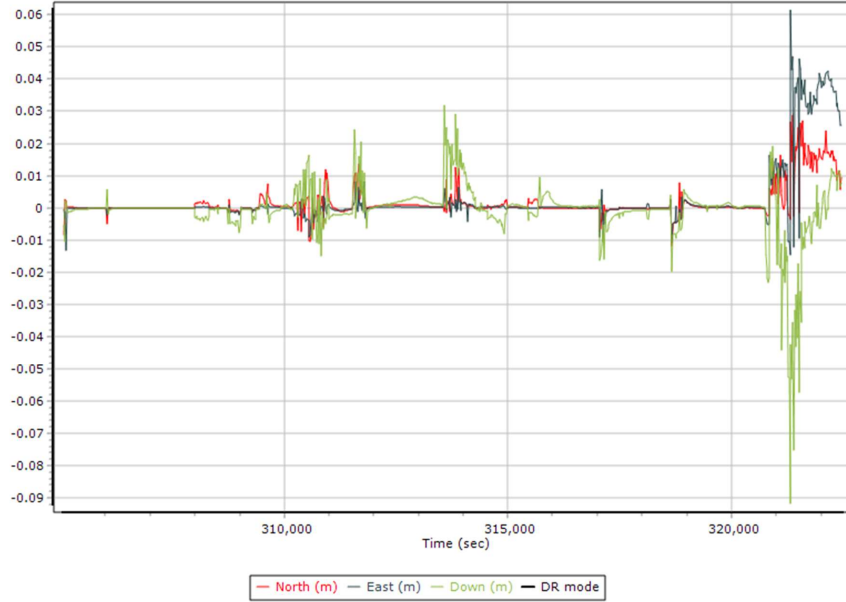
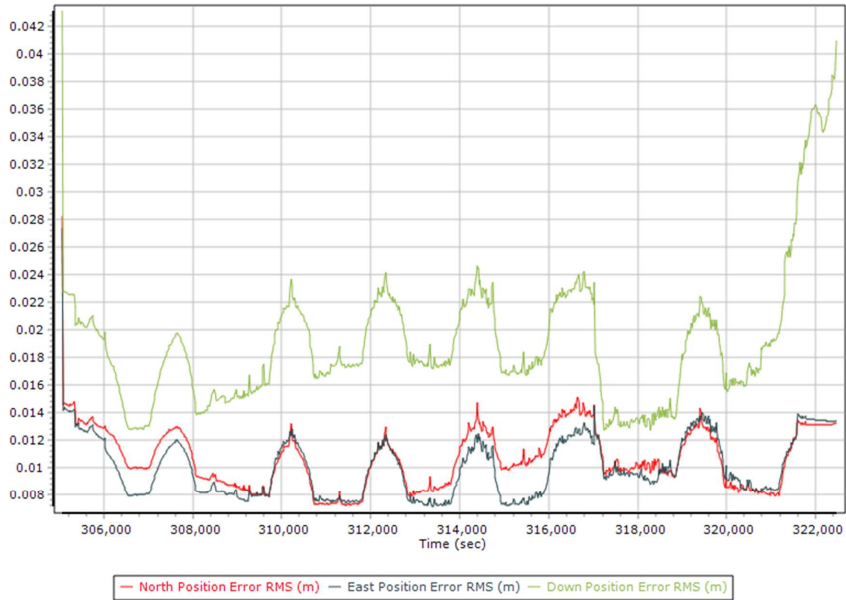
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

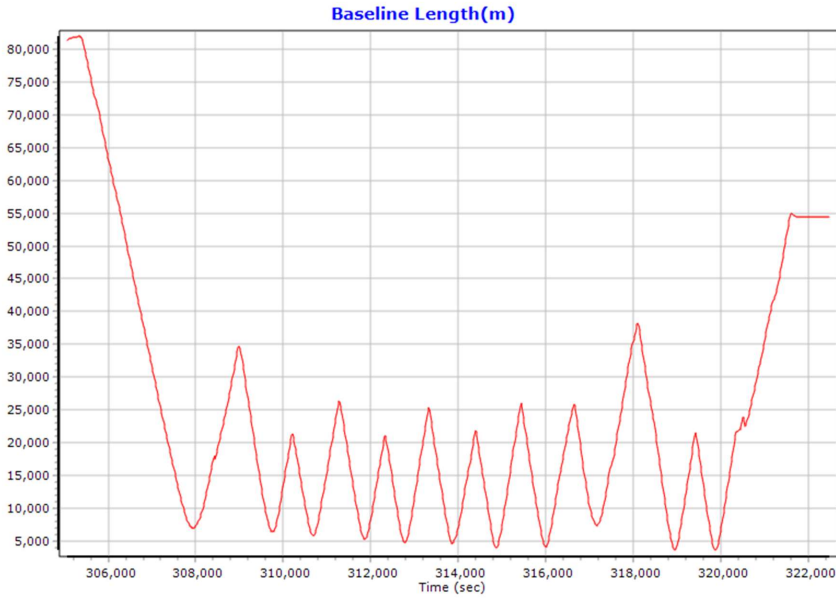
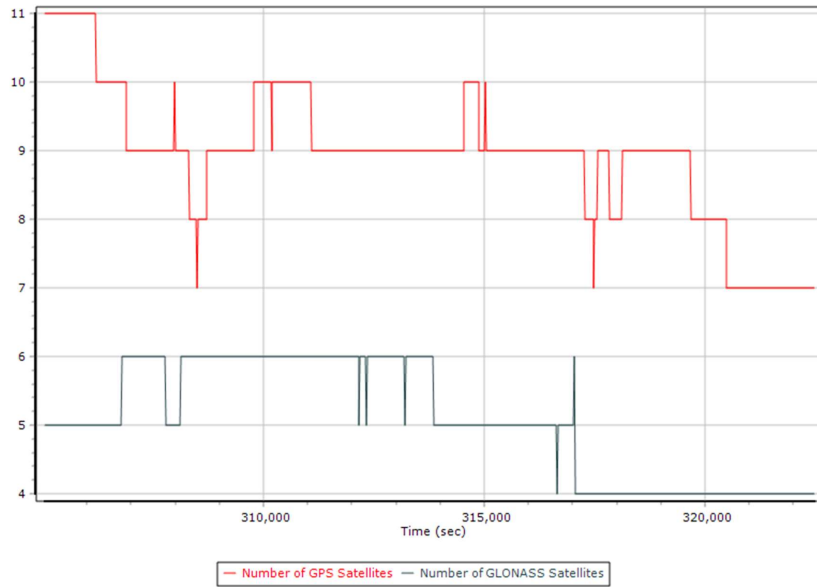
Entire time interval
Seconds of start week

OK Cancel

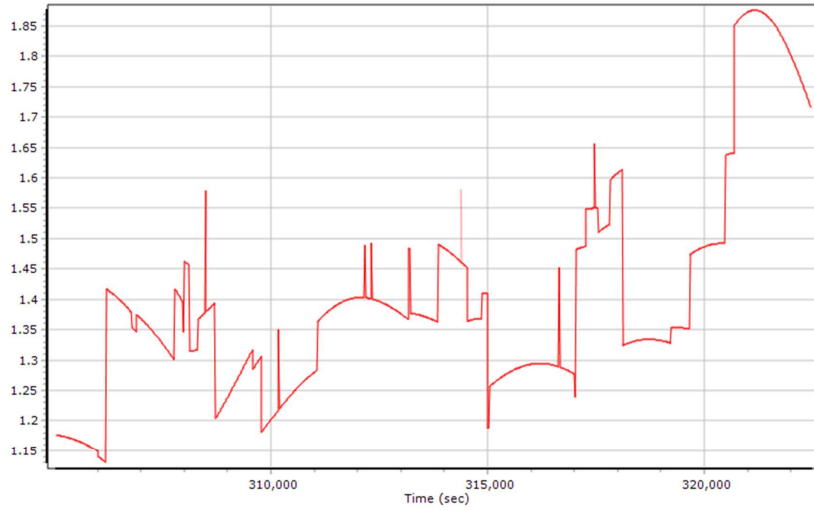






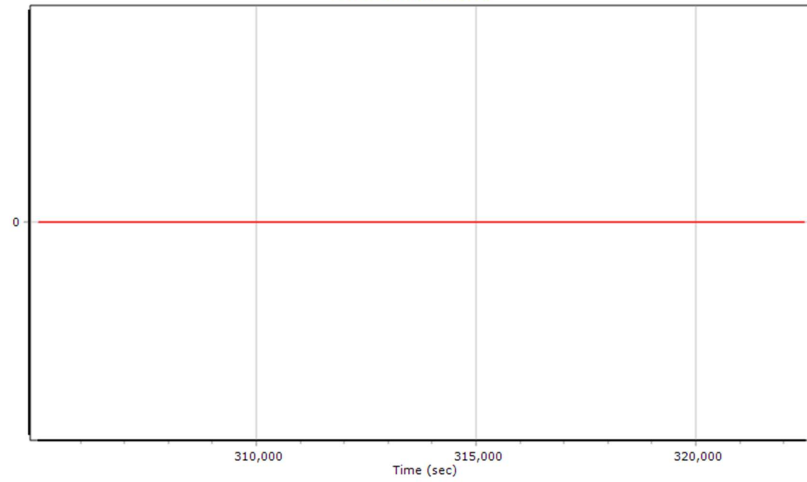


PDOP



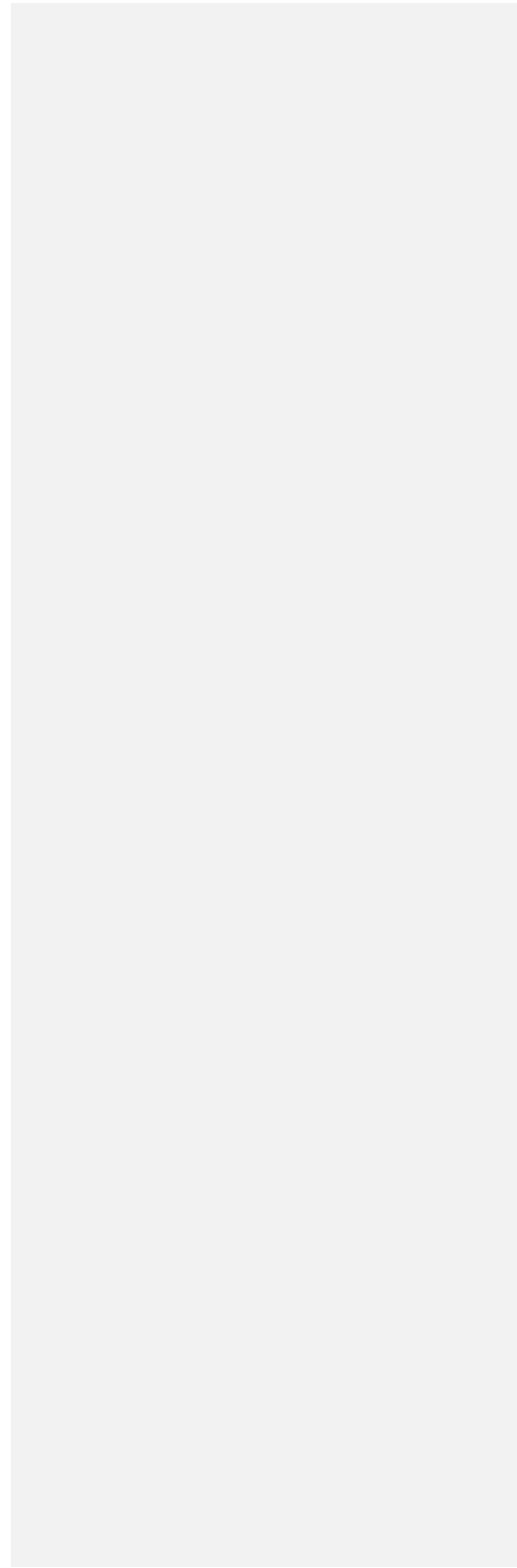
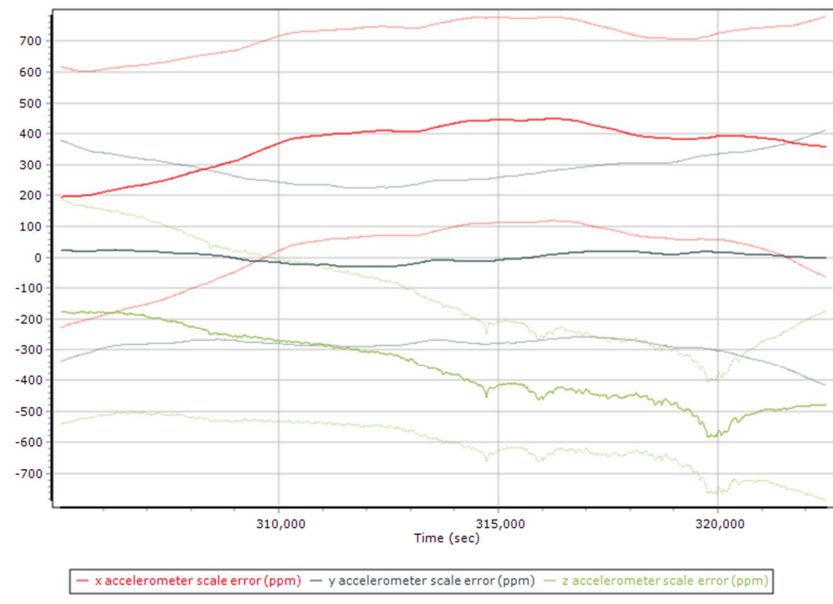
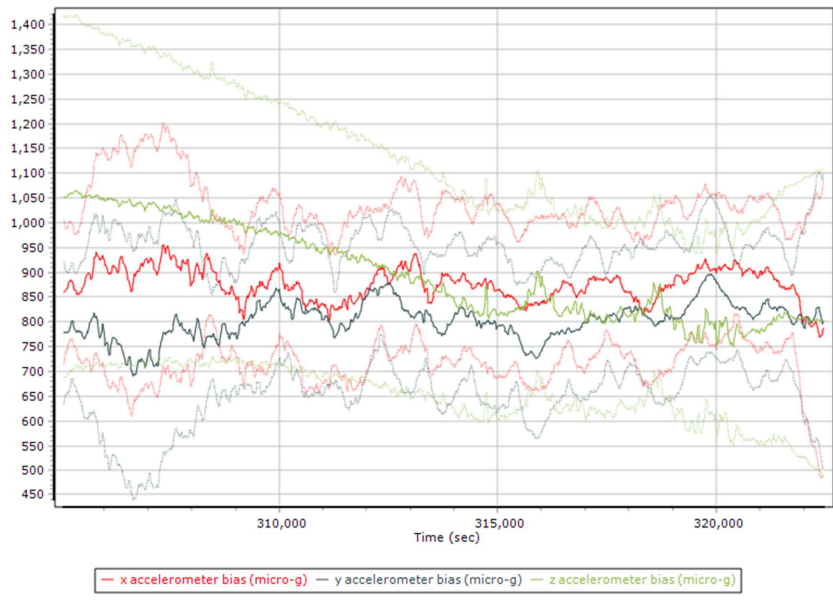
Forward Reverse

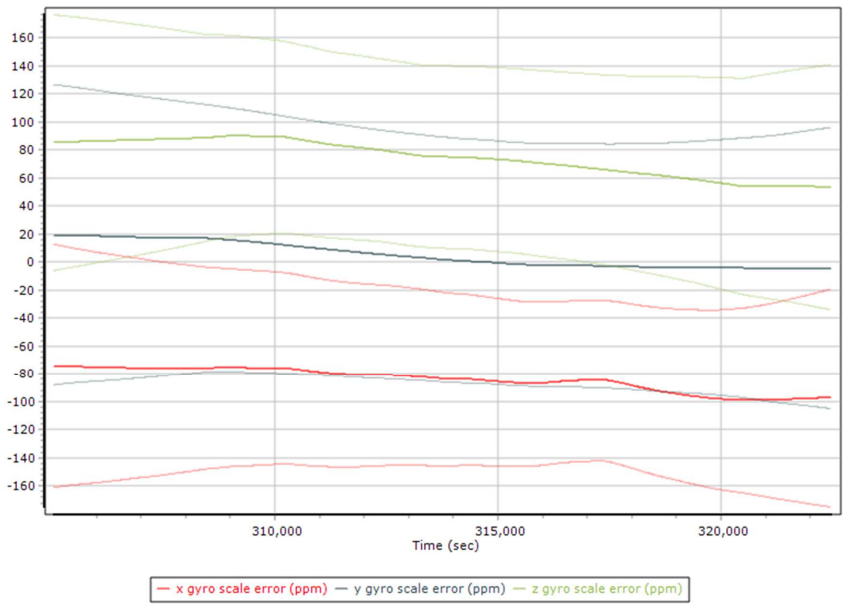
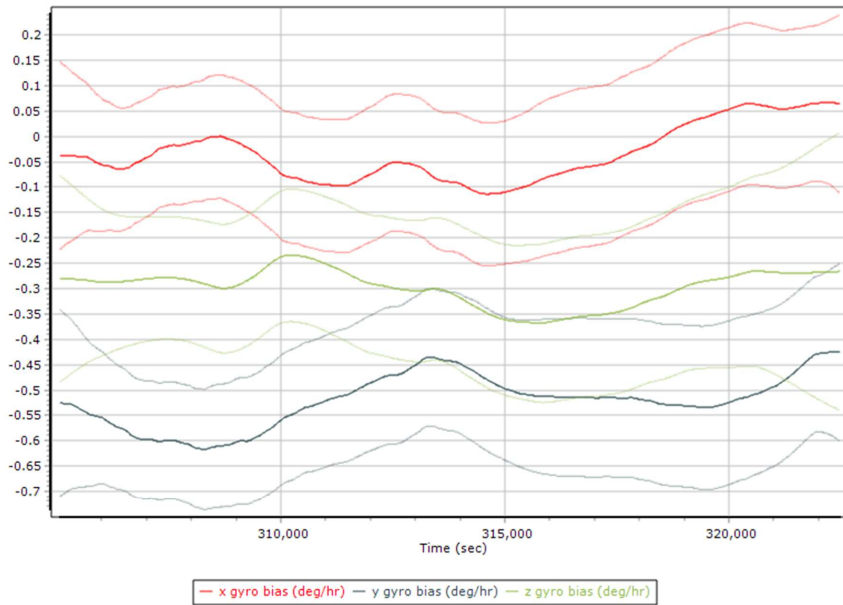
Processing Mode



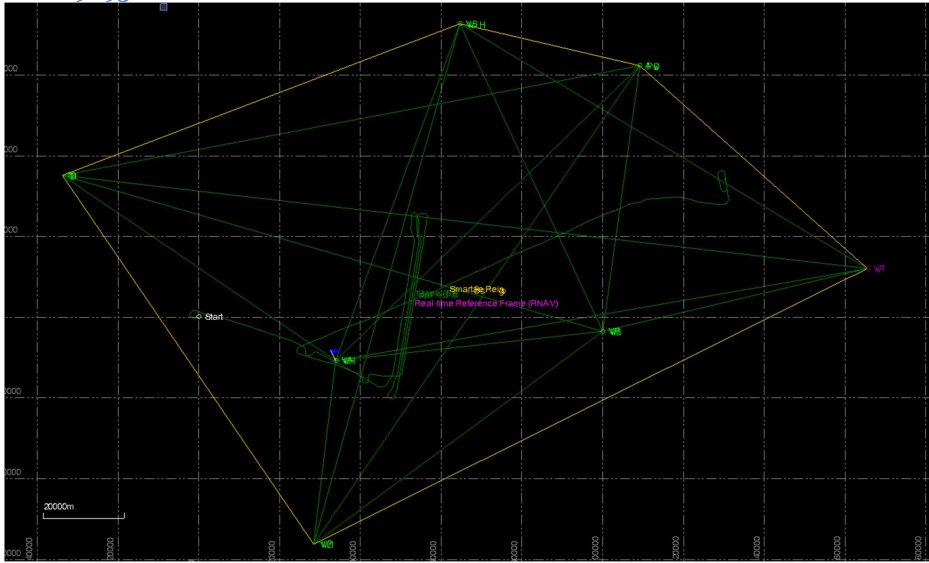
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR





MNB19093B



Project Settings [X]

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
 - Export
 - Camera
 - LIDAR
 - SAR

| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
|----------------------------|----------------------------------|
| X: 0.034 m | X: 0.000 deg |
| Y: 0.018 m | Y: 0.000 deg |
| Z: -0.155 m | Z: 0.000 deg |

| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
|-------------------------------------|---------------------------------------|
| X: -0.150 m | X: 0.000 deg |
| Y: -0.061 m | Y: 0.000 deg |
| Z: -0.992 m | Z: 0.000 deg |

Standard Deviation: [Slider] <3cm 10cm 50cm 1m 10m

OK Cancel

Project Settings

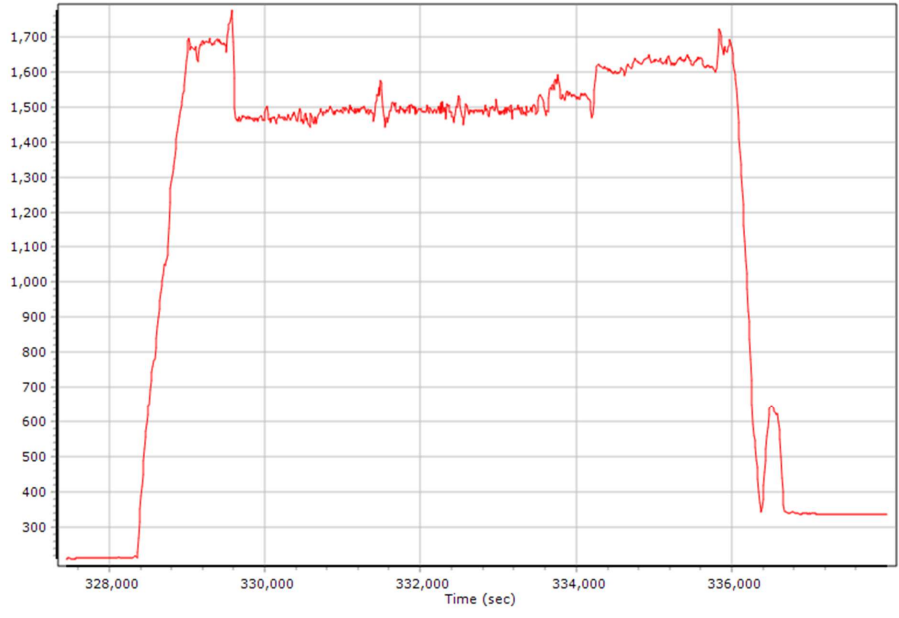
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing**
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export

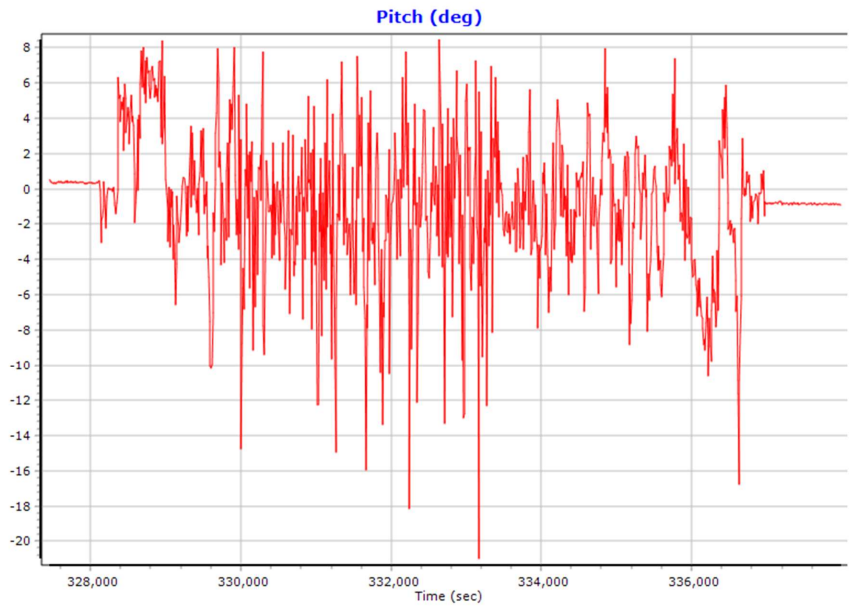
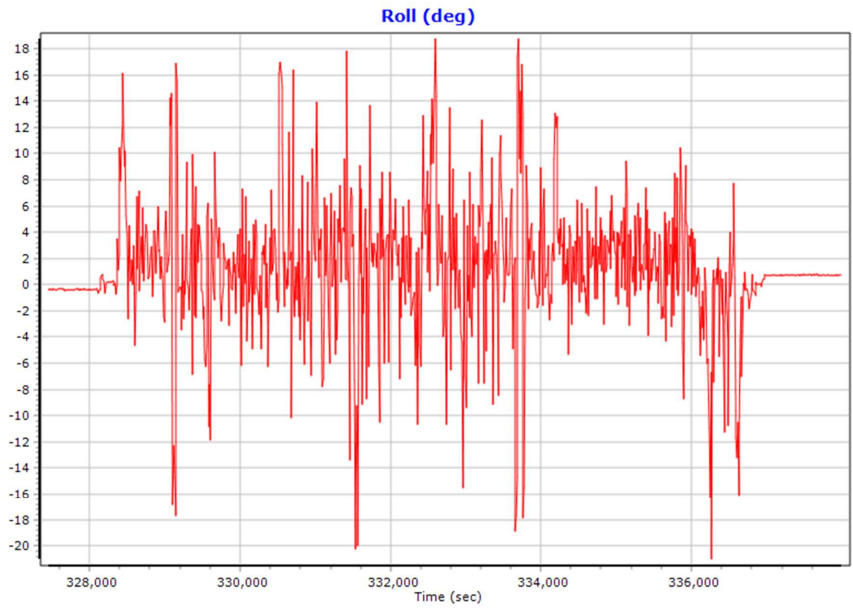
Timing

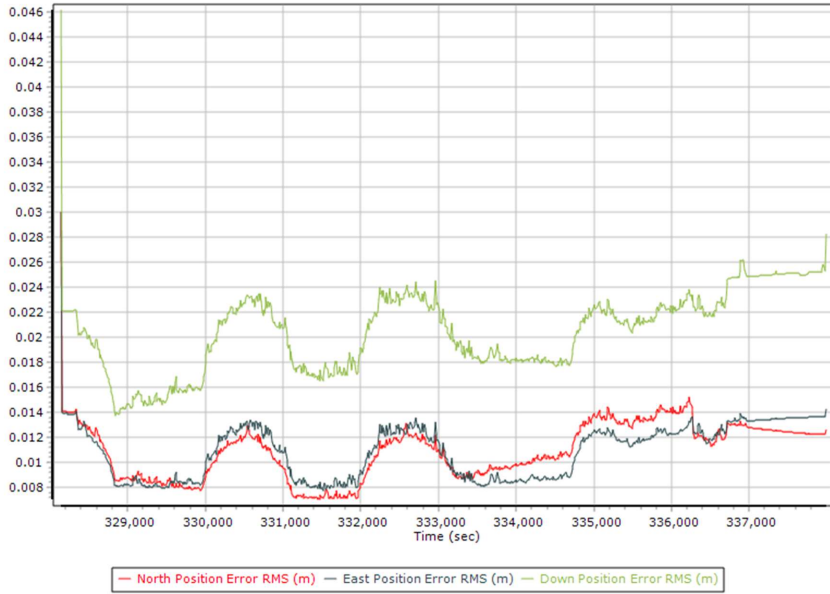
Start: 327453.000
 End: 337994.000
 Entire time interval
 Seconds of start week
 UTC Offset: 18.000

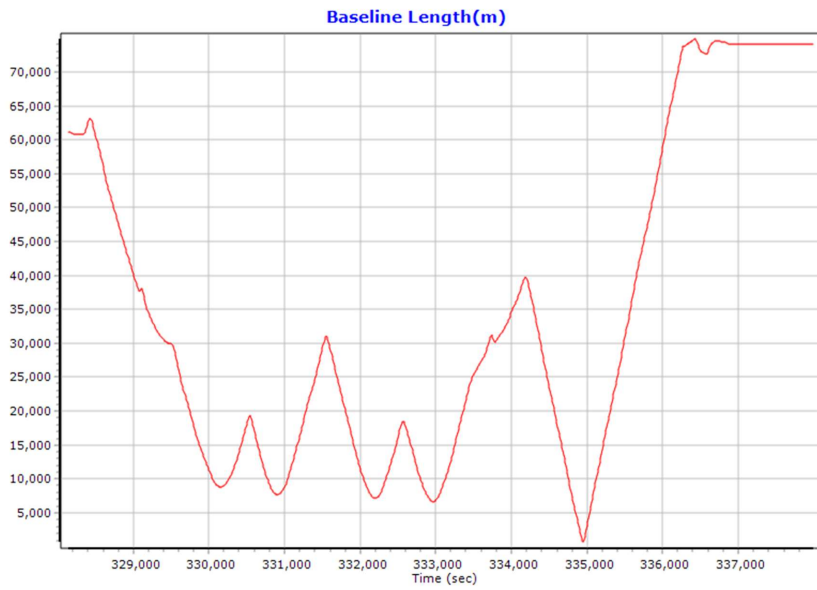
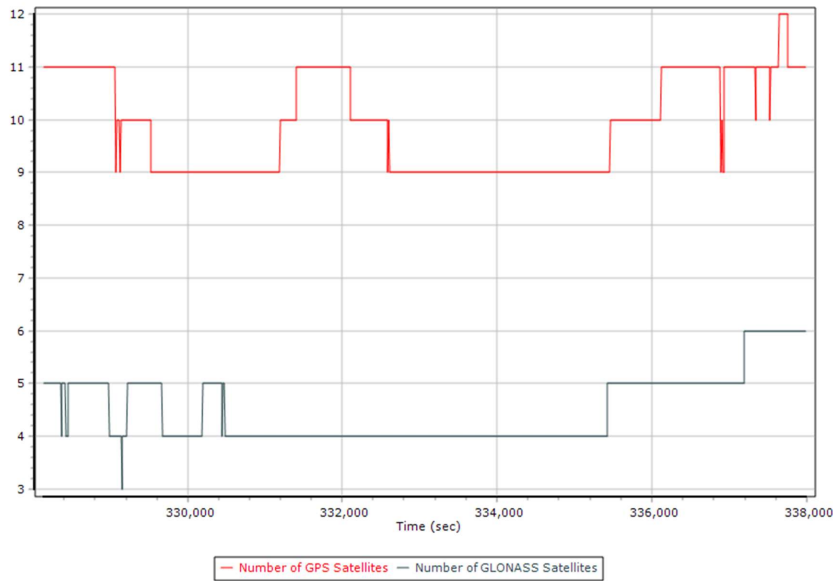
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

Altitude (m)





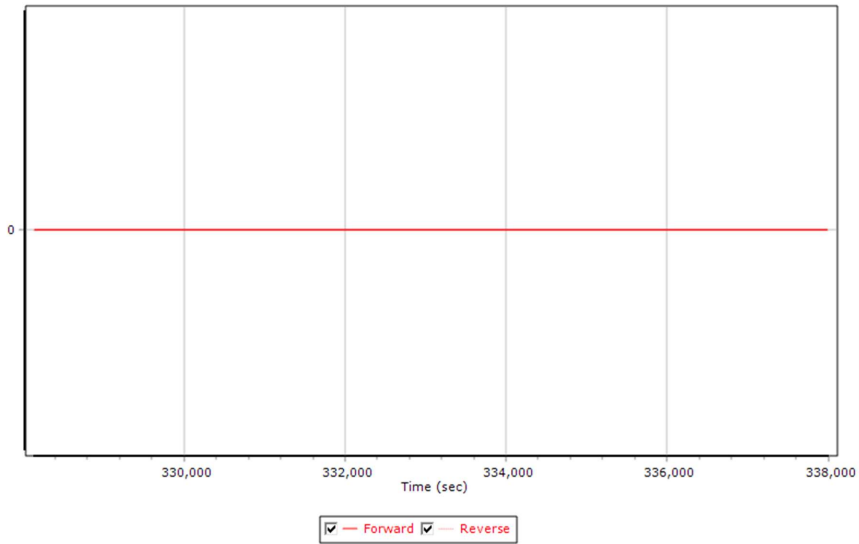




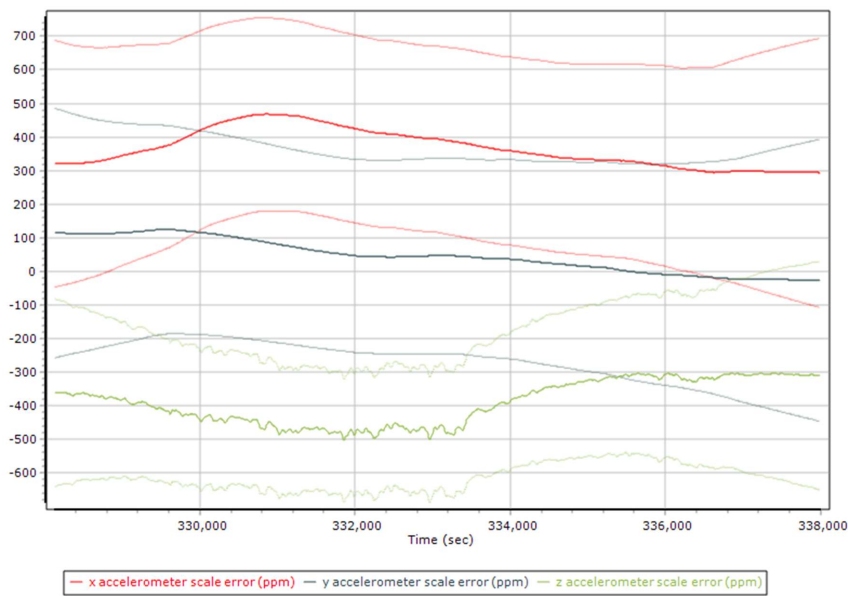
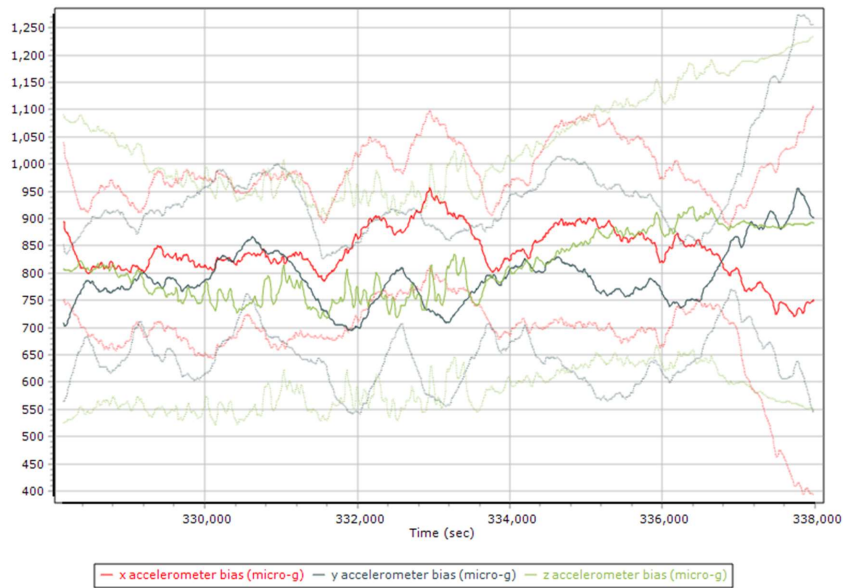
PDOP

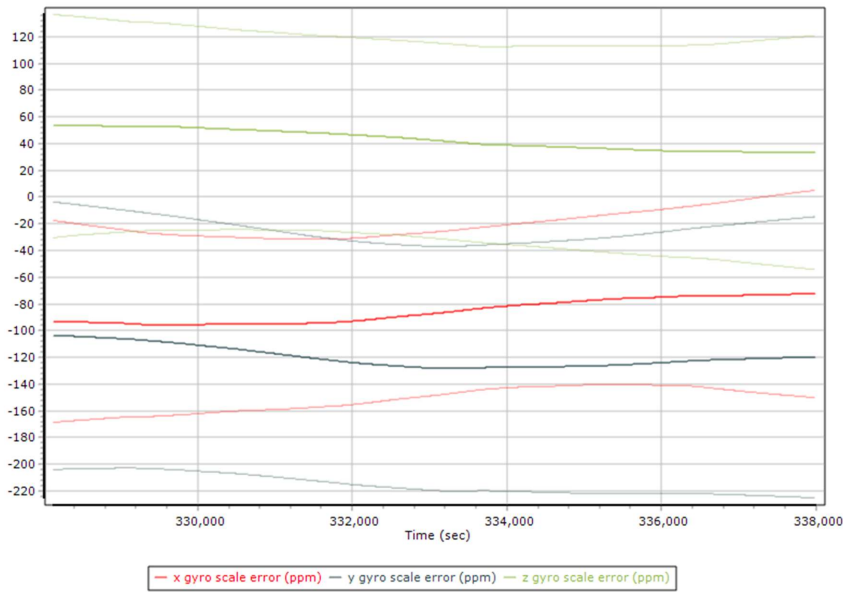
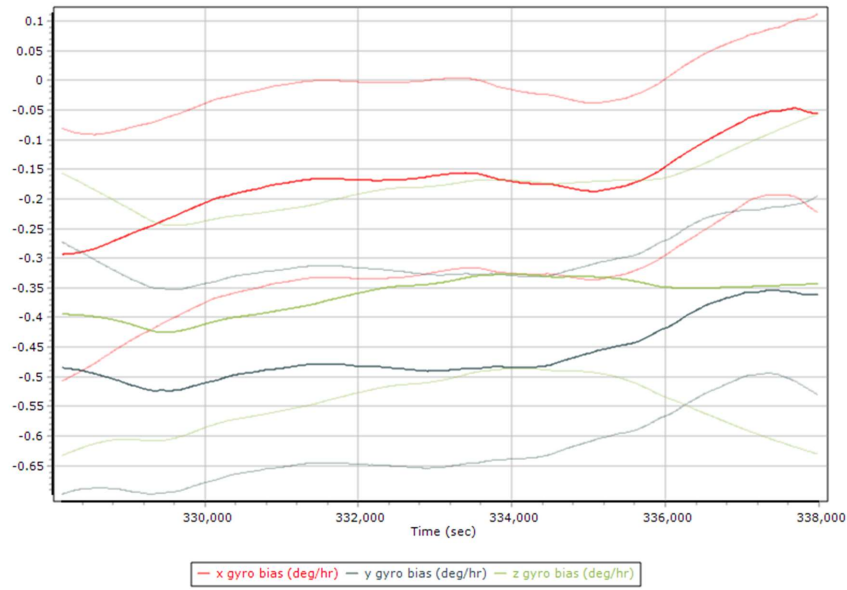


Processing Mode

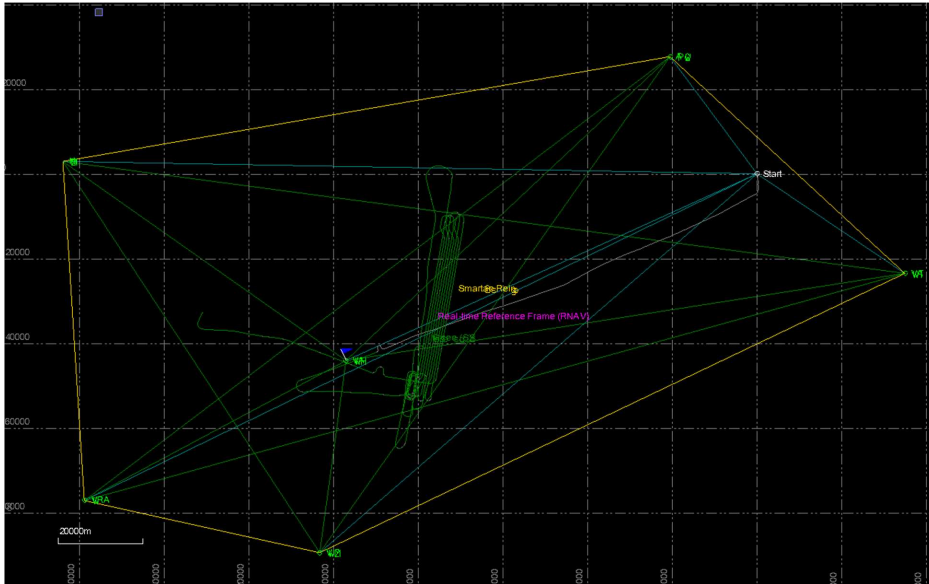


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR





MNB19094A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
 - Export
- Camera
- LiDAR
- SAR

| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
|----------------------------|----------------------------------|
| X: 0.034 m | X: 0.000 deg |
| Y: 0.018 m | Y: 0.000 deg |
| Z: -0.155 m | Z: 0.000 deg |

| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
|-------------------------------------|---------------------------------------|
| X: -0.150 m | X: 0.000 deg |
| Y: -0.061 m | Y: 0.000 deg |
| Z: -0.992 m | Z: 0.000 deg |

Standard Deviation: <3cm 10cm 50cm 1m 10m

OK Cancel

Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms

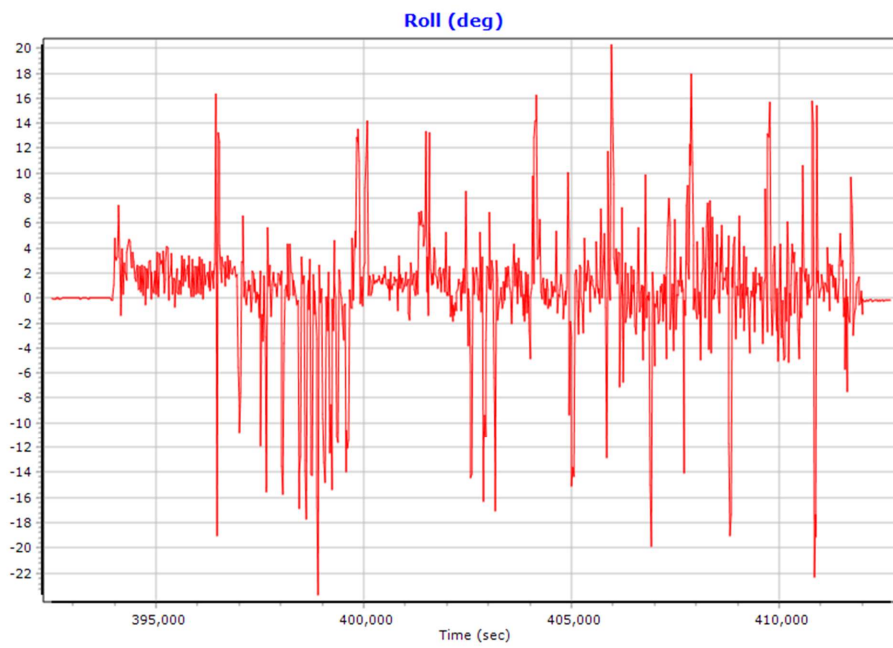
Timing

Start: 396517.150
End: 412691.000

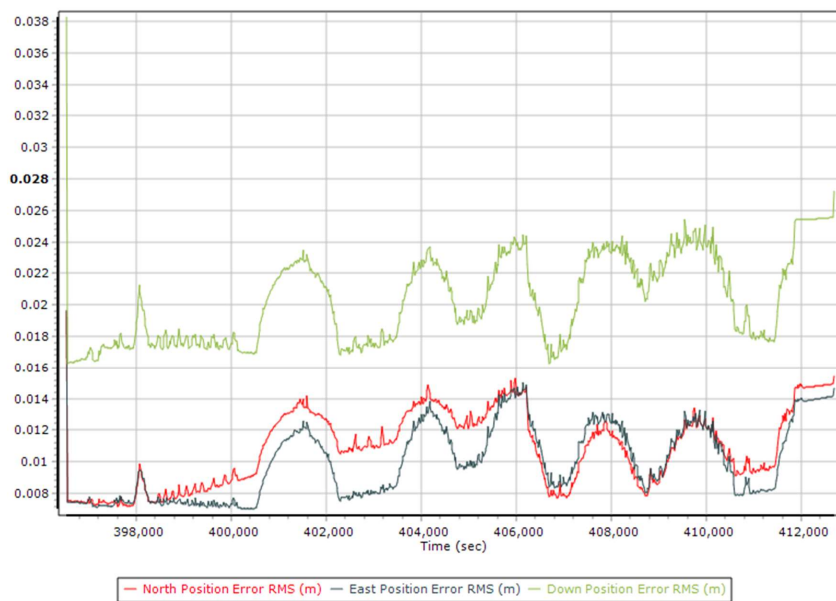
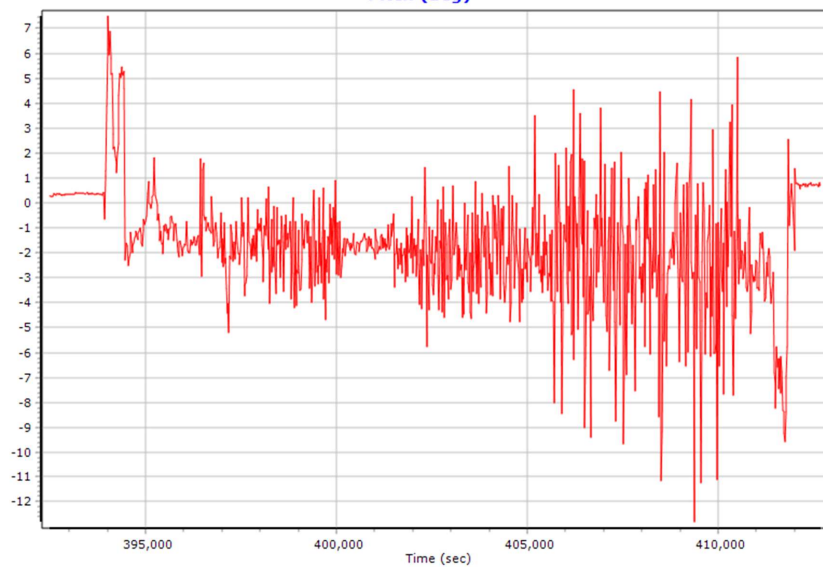
Entire time interval
 Seconds of start week

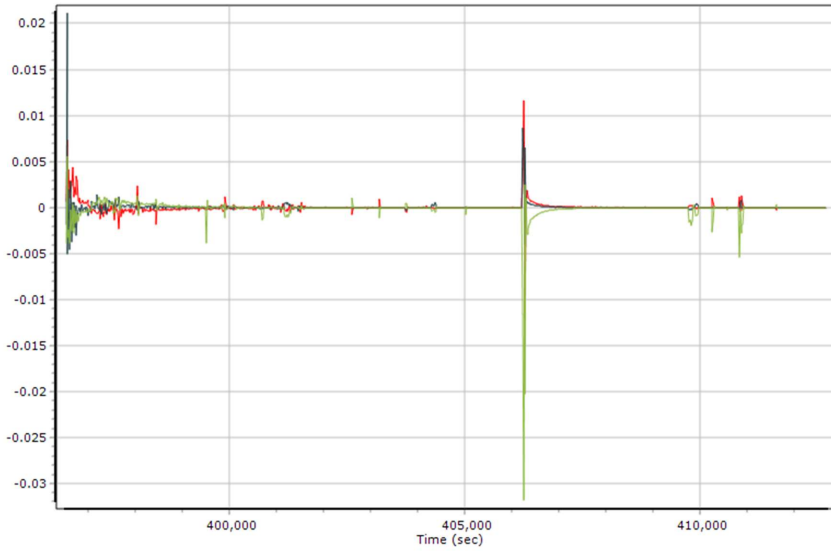
UTC Offset: 18.000

| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

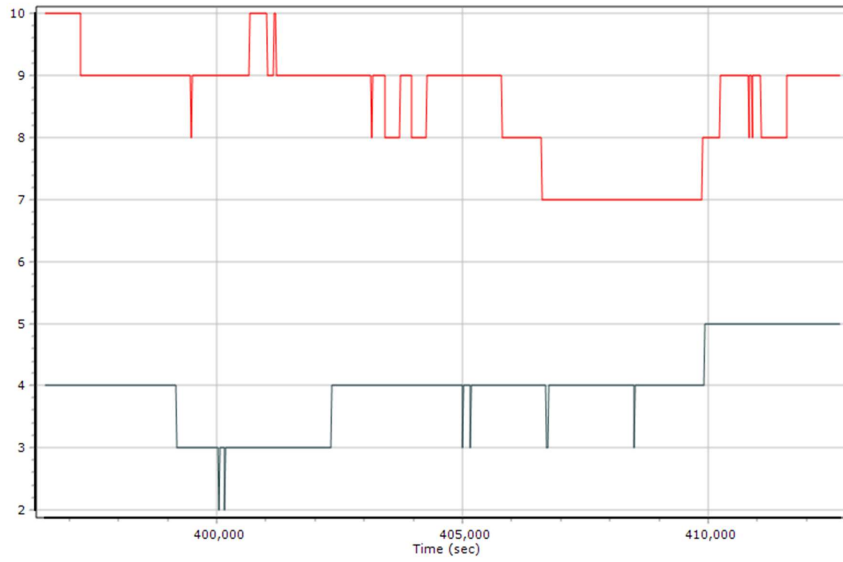


Pitch (deg)

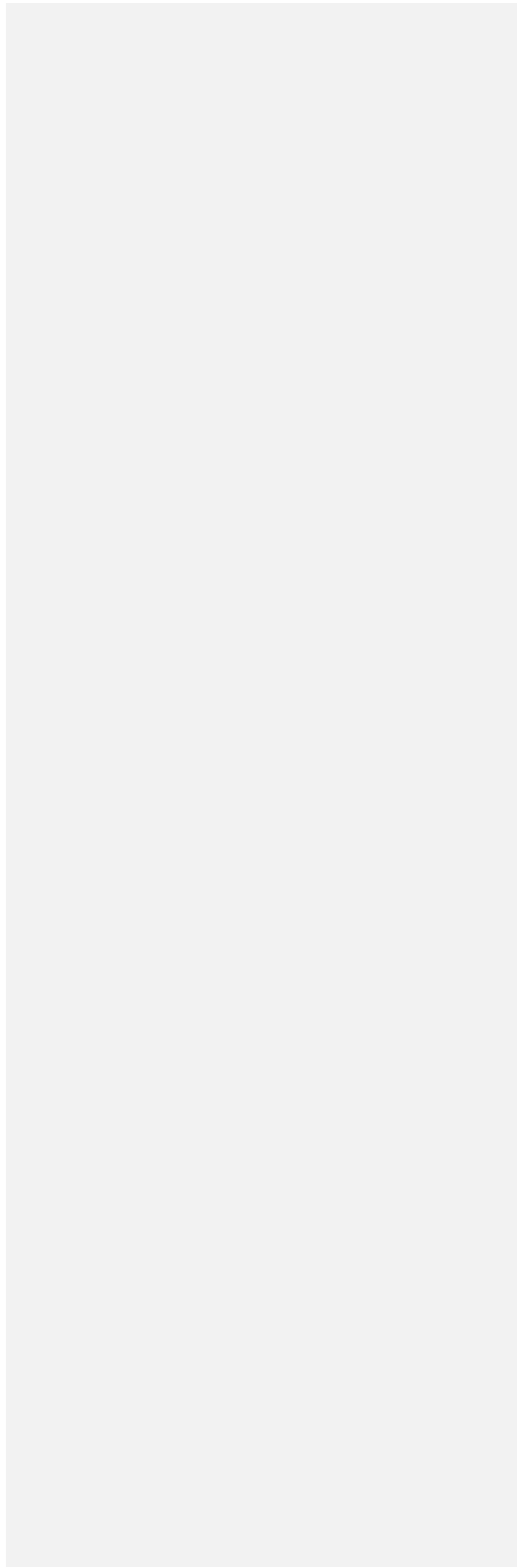




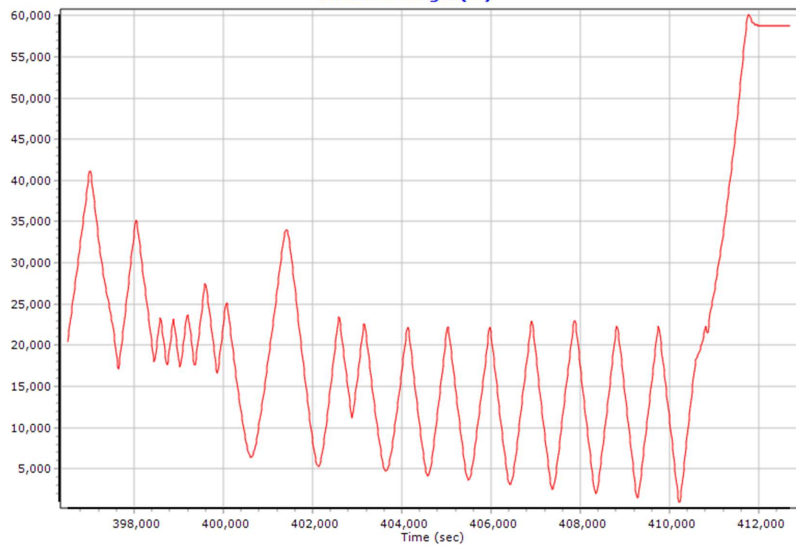
— North (m) — East (m) — Down (m) — DR mode



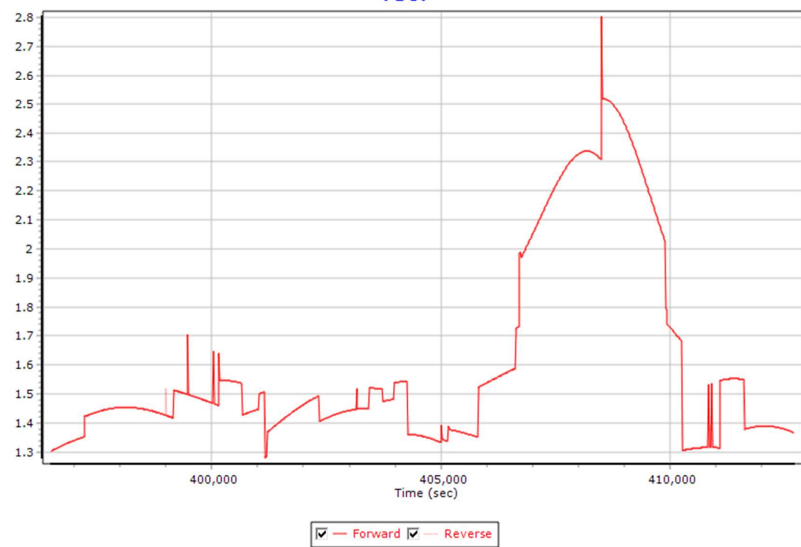
— Number of GPS Satellites — Number of GLONASS Satellites



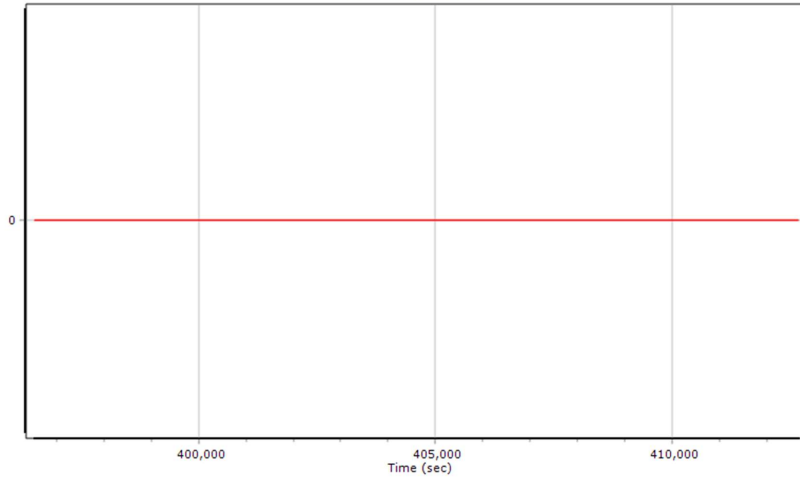
Baseline Length(m)



PDOP

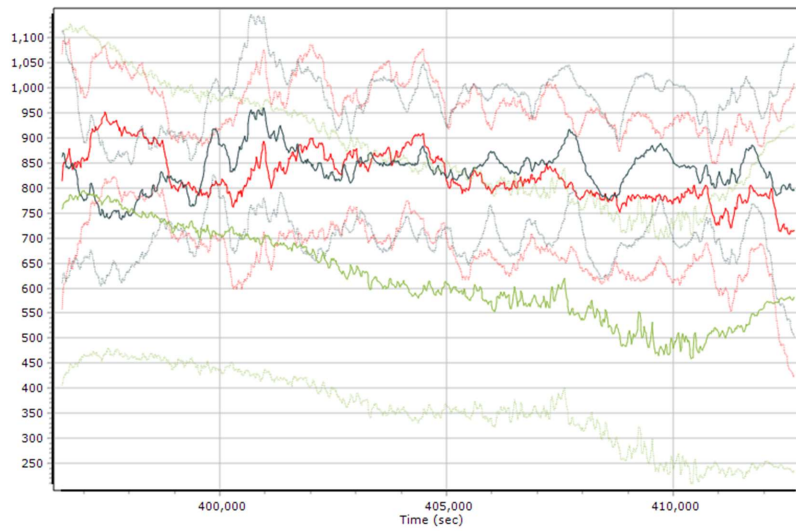


Processing Mode

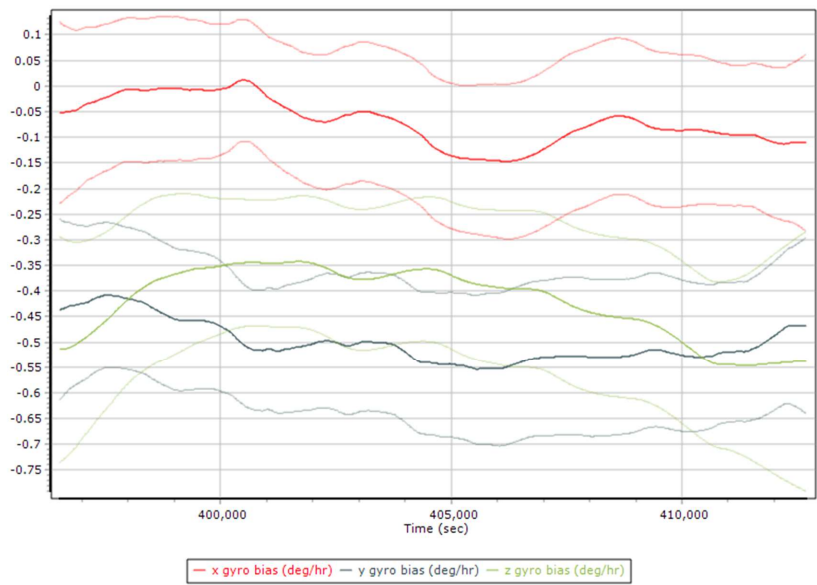
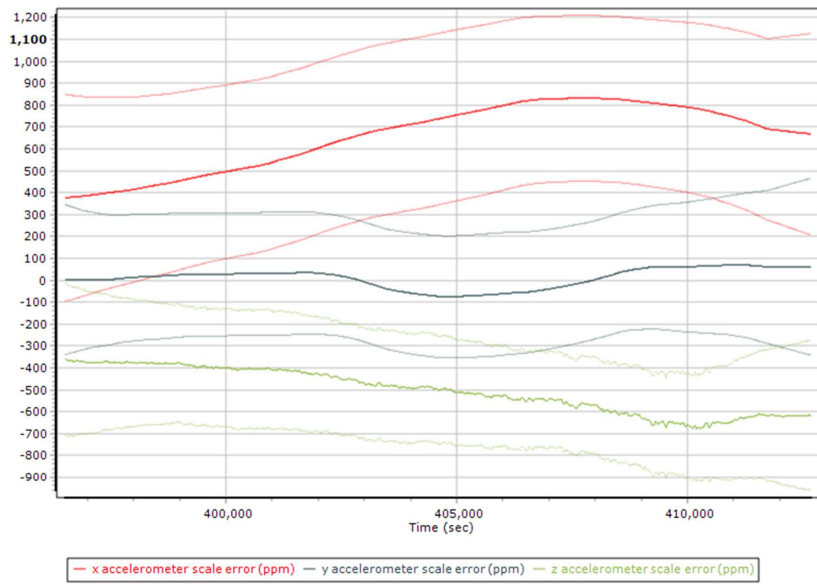


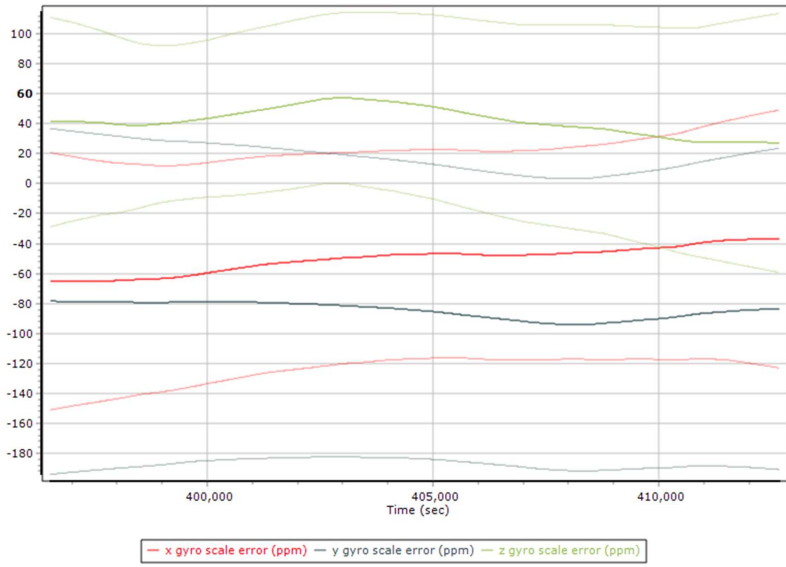
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

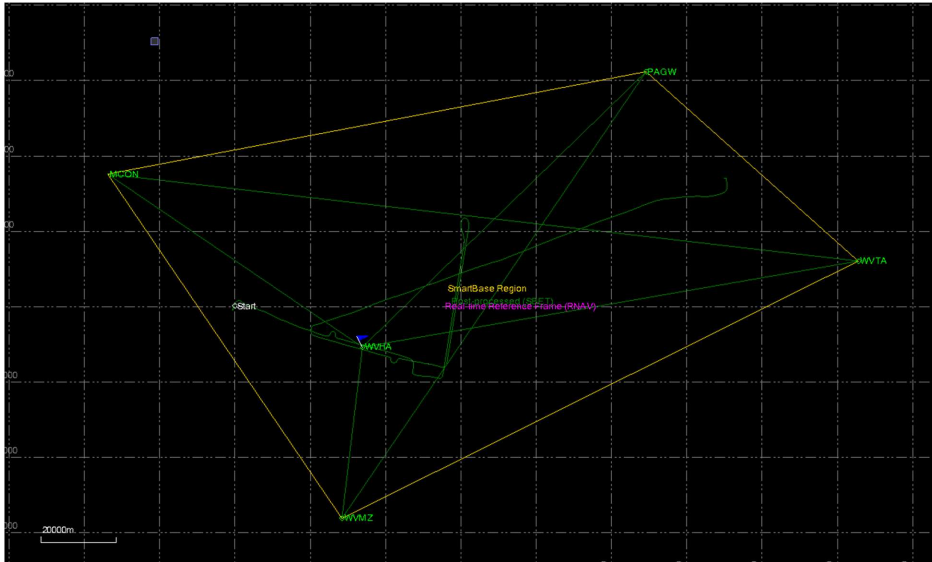


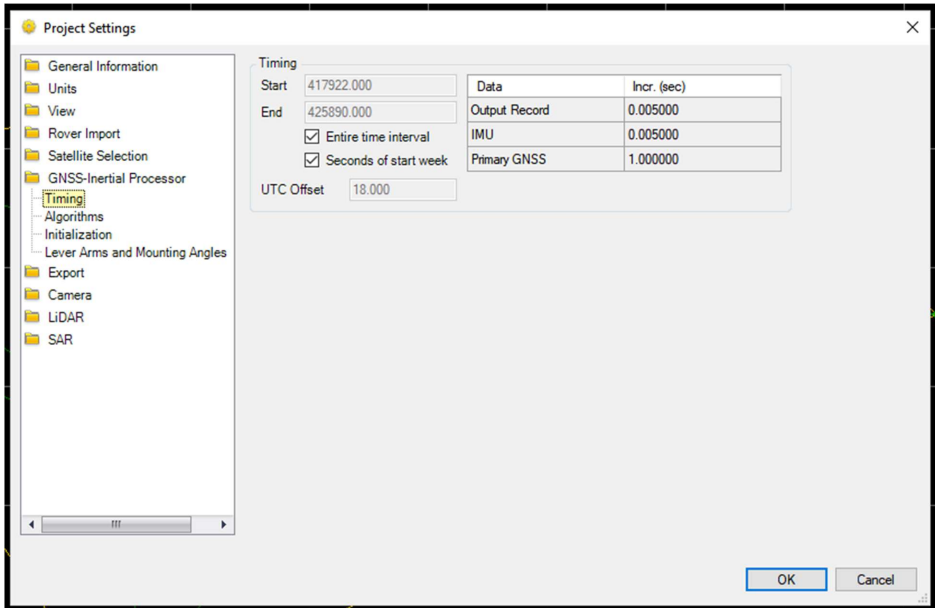
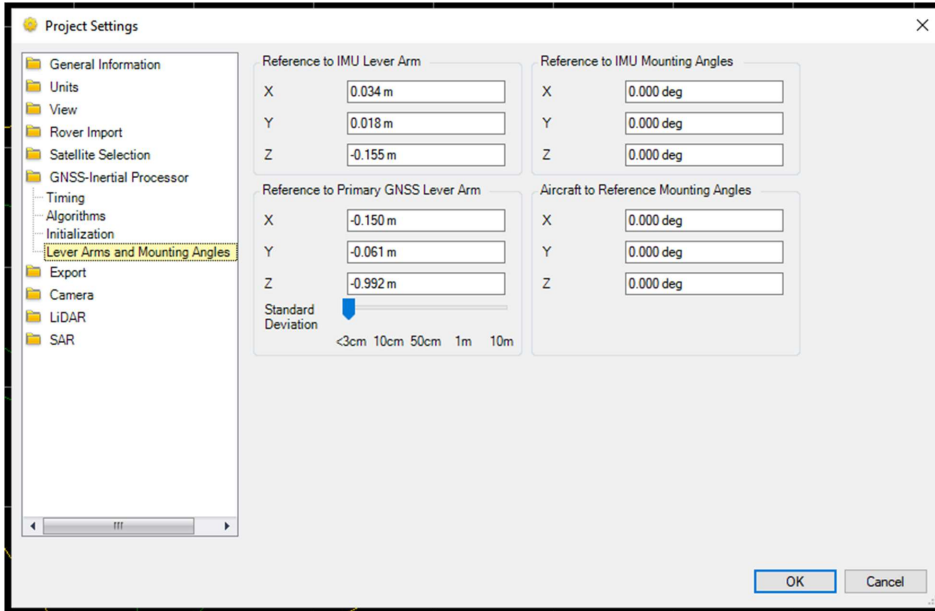
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)

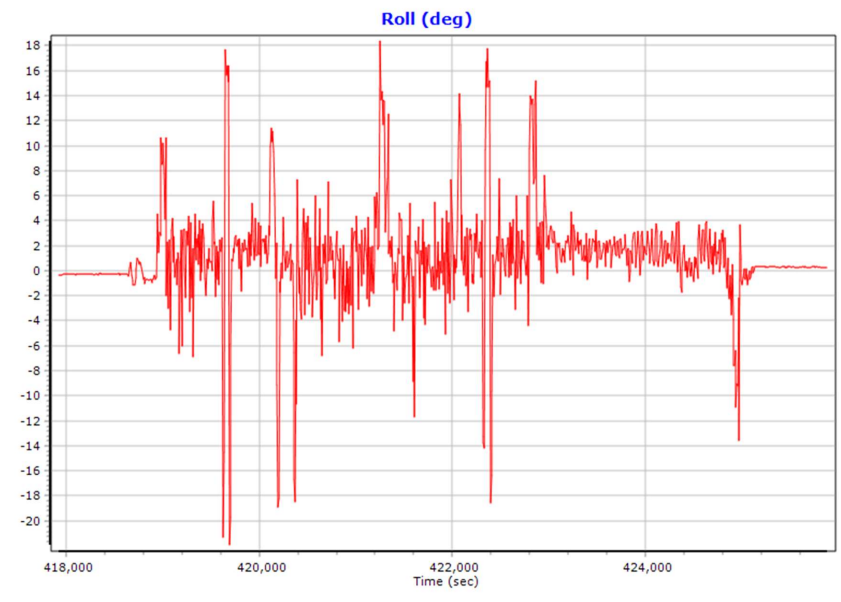
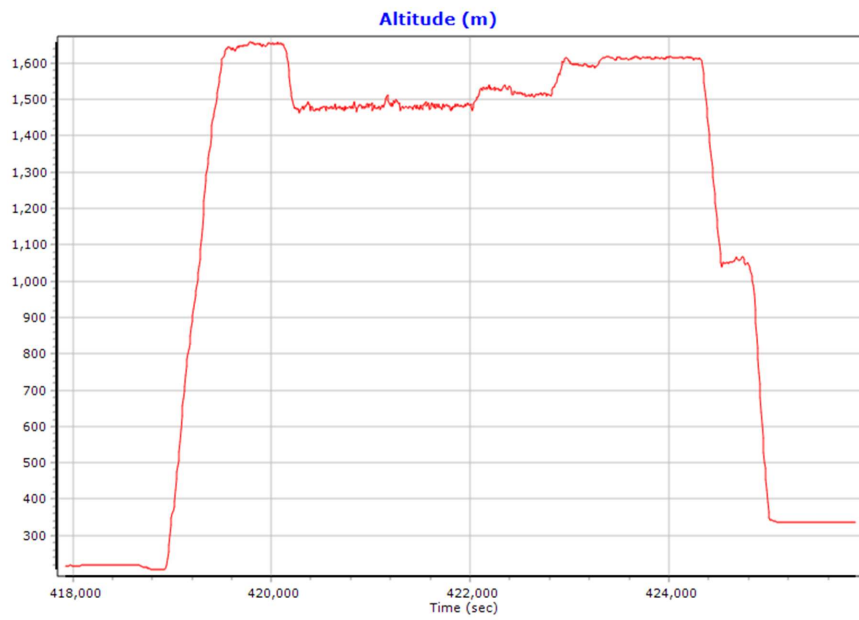




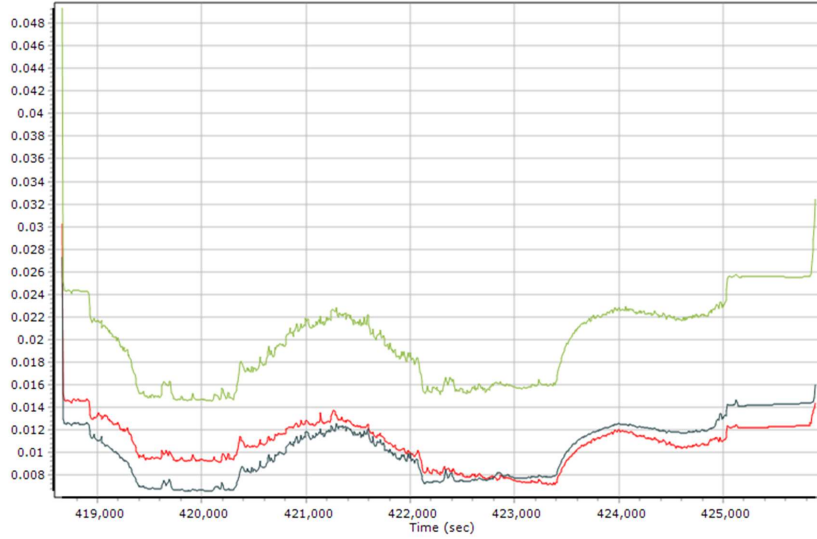
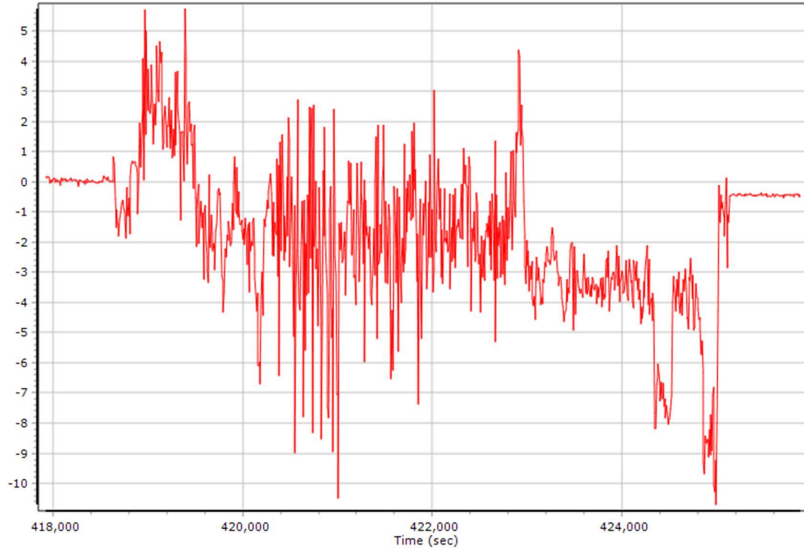
MNB19094B



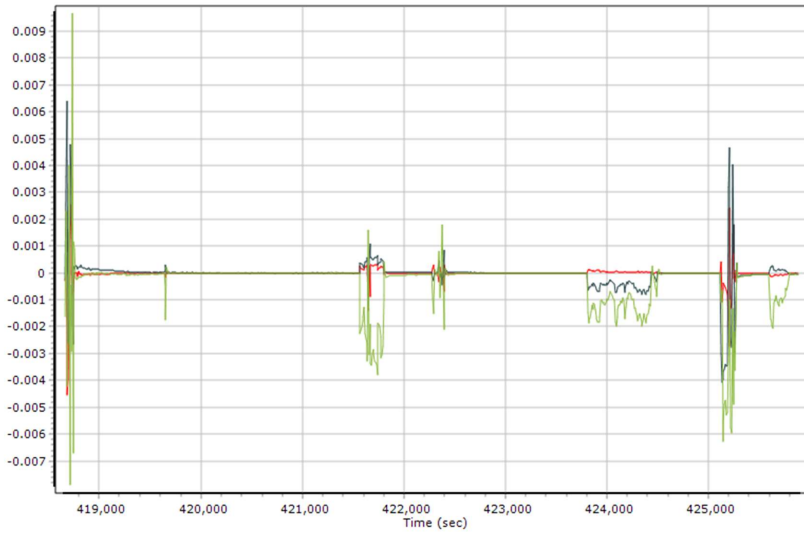




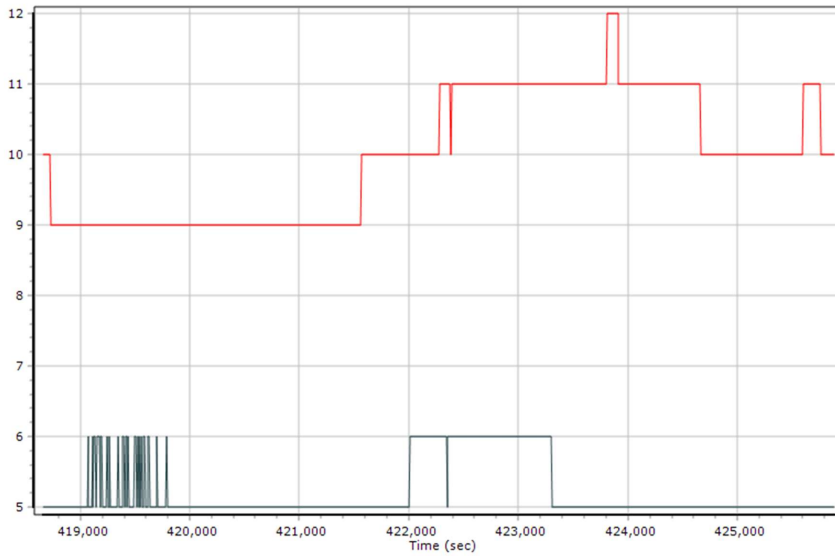
Pitch (deg)



— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)

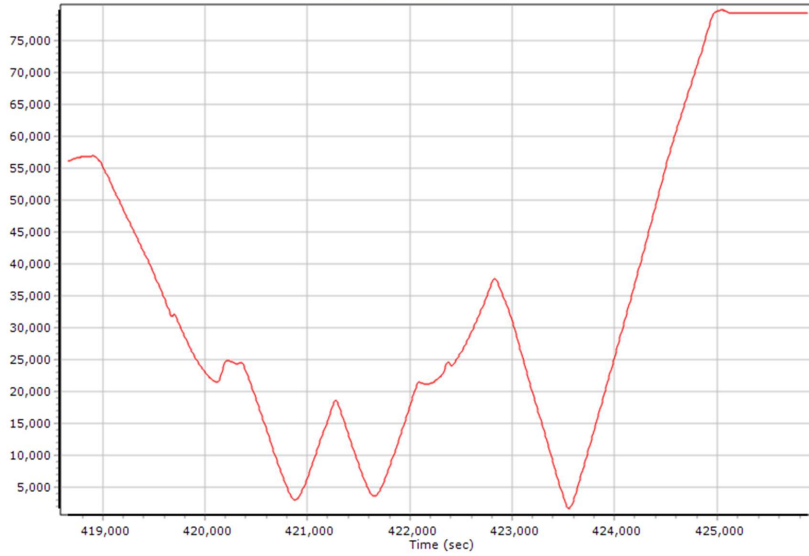


— North (m) — East (m) — Down (m) — DR mode

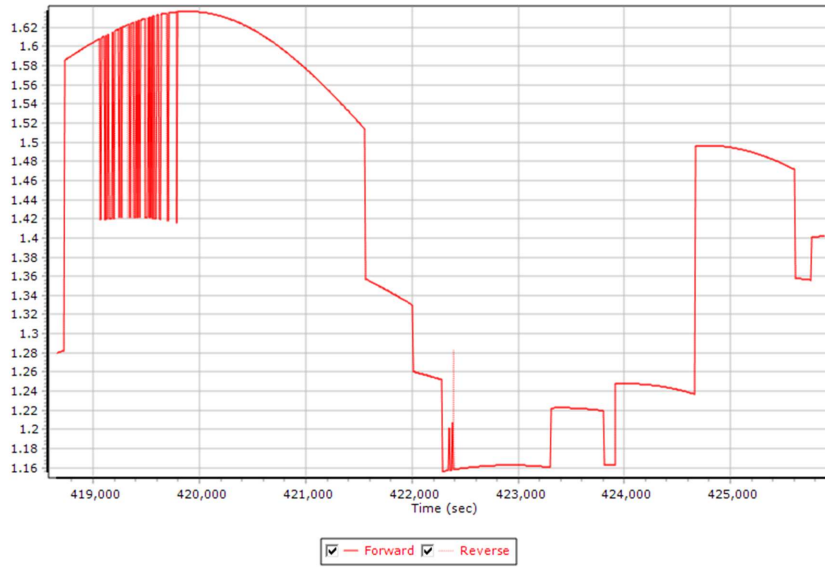


— Number of GPS Satellites — Number of GLONASS Satellites

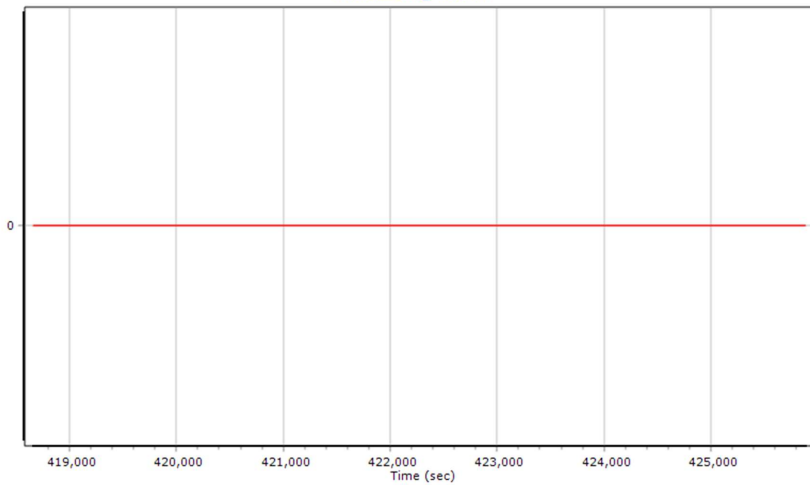
Baseline Length(m)



PDOP



Processing Mode

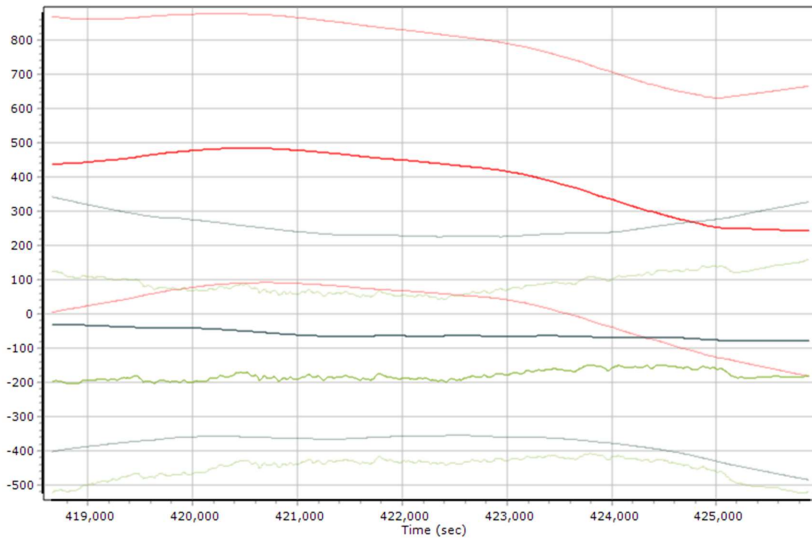


Forward Reverse

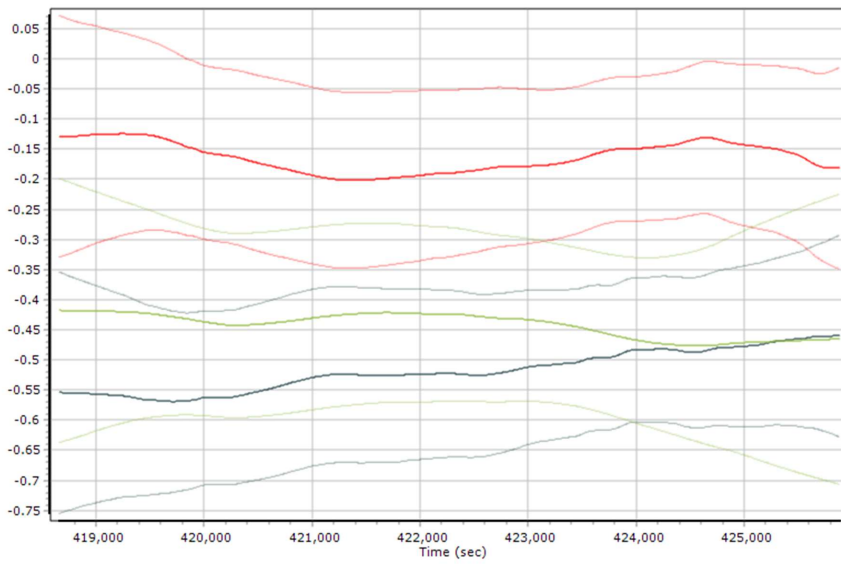
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



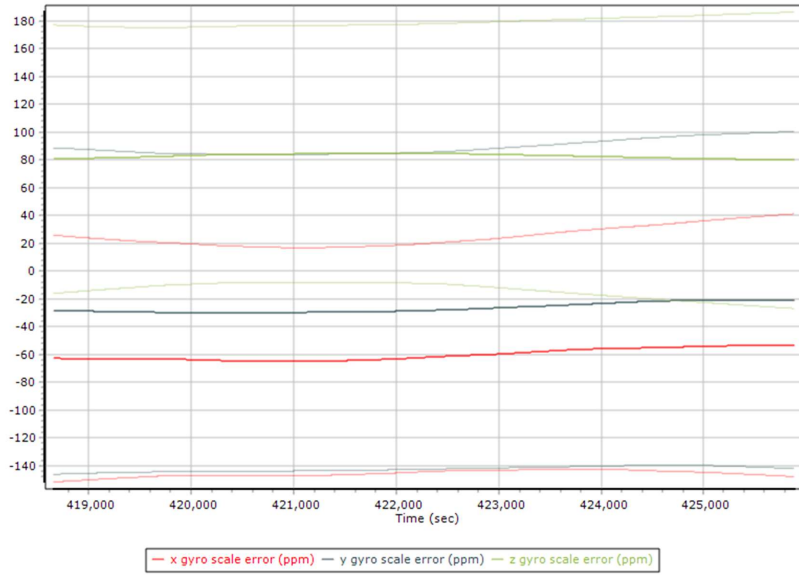
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)



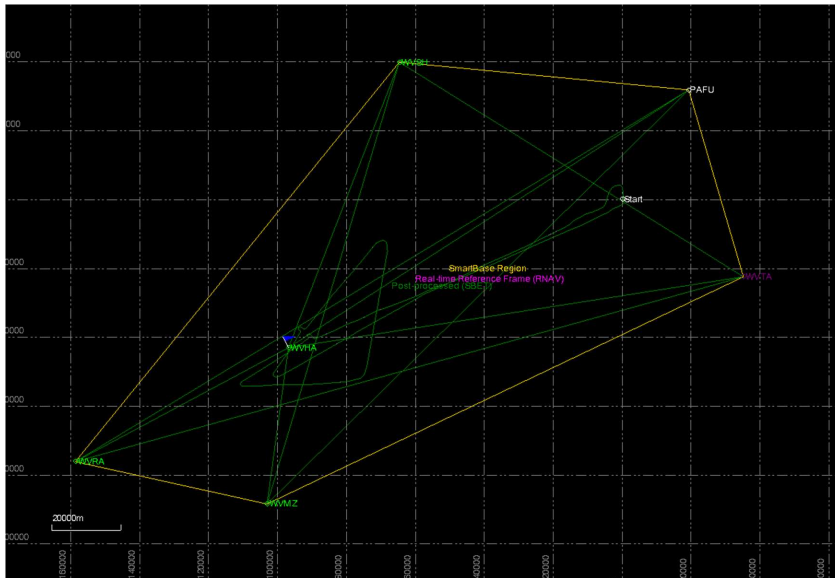
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



MNB19095A



Project Settings [X]

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
 - Export
 - Camera
 - LiDAR
 - SAR

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation: <3cm 10cm 50cm 1m 10m

Aircraft to Reference Mounting Angles

X:

Y:

Z:

OK Cancel

Project Settings [X]

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing**
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
 - Export
 - Camera
 - LiDAR
 - SAR

Timing

Start: Data: Incr. (sec):

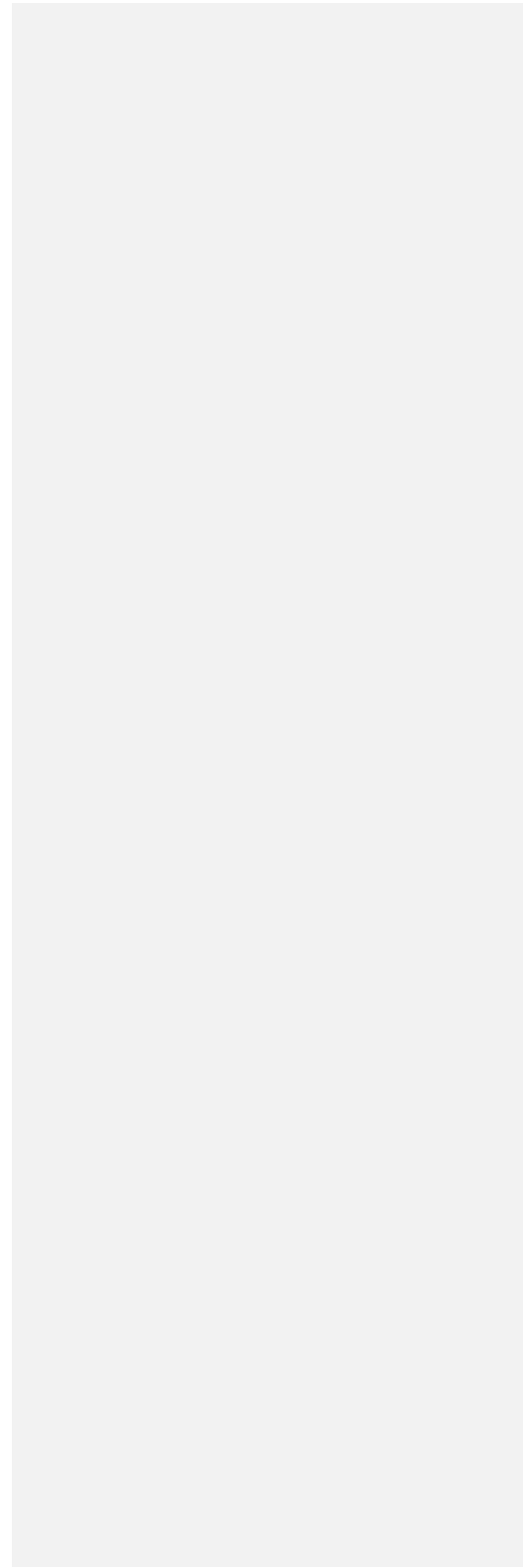
End:

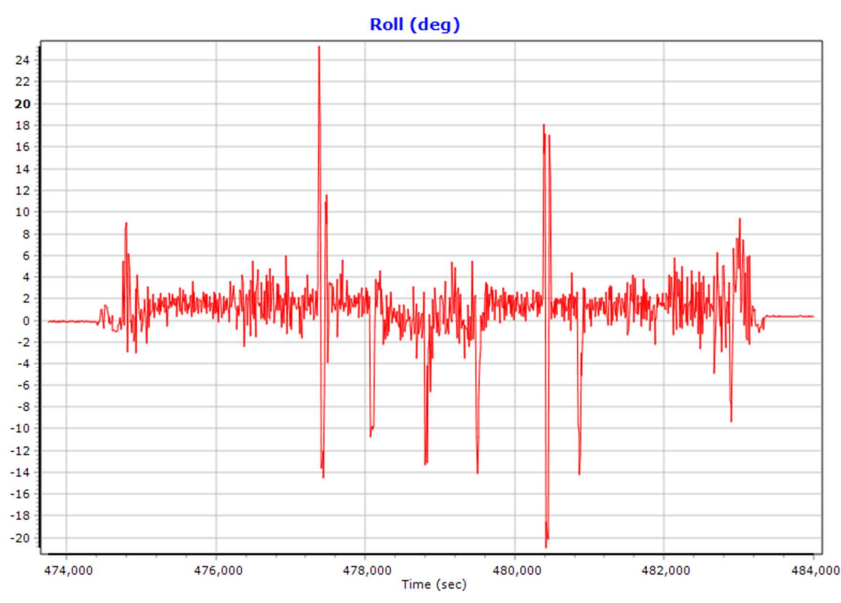
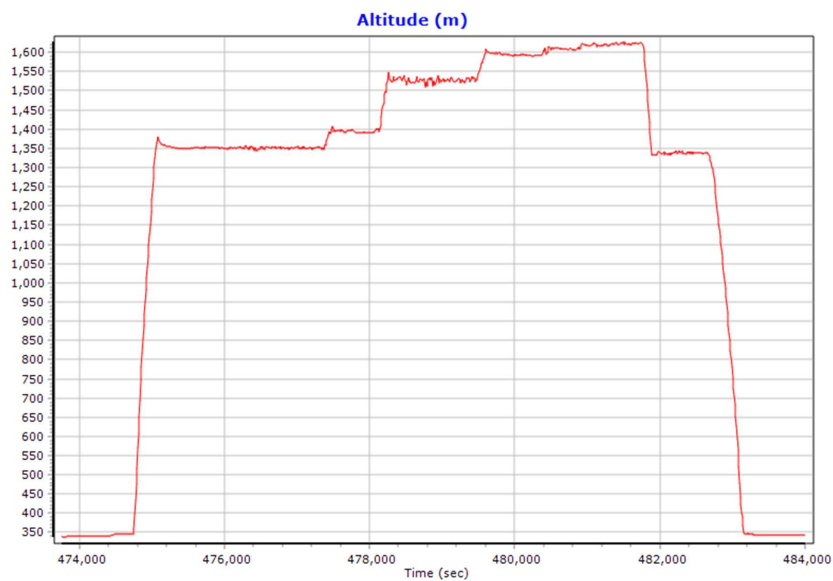
Entire time interval

Seconds of start week

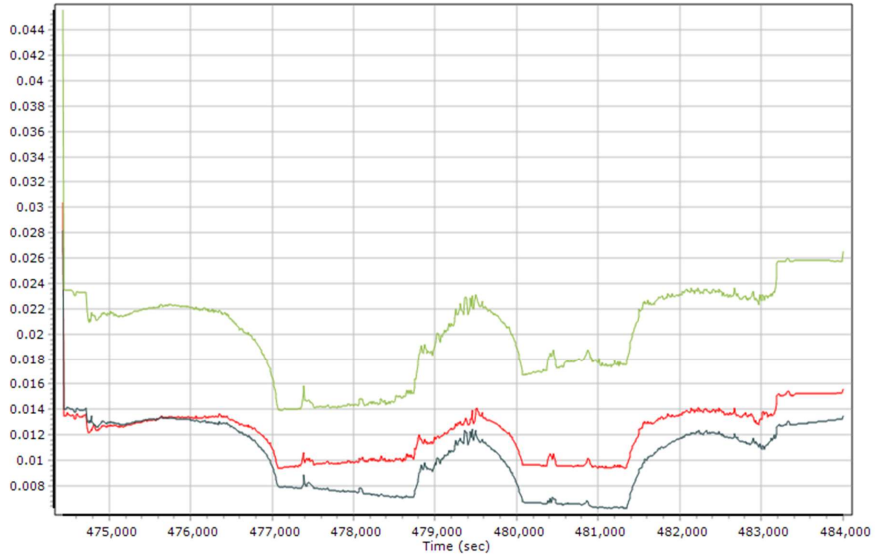
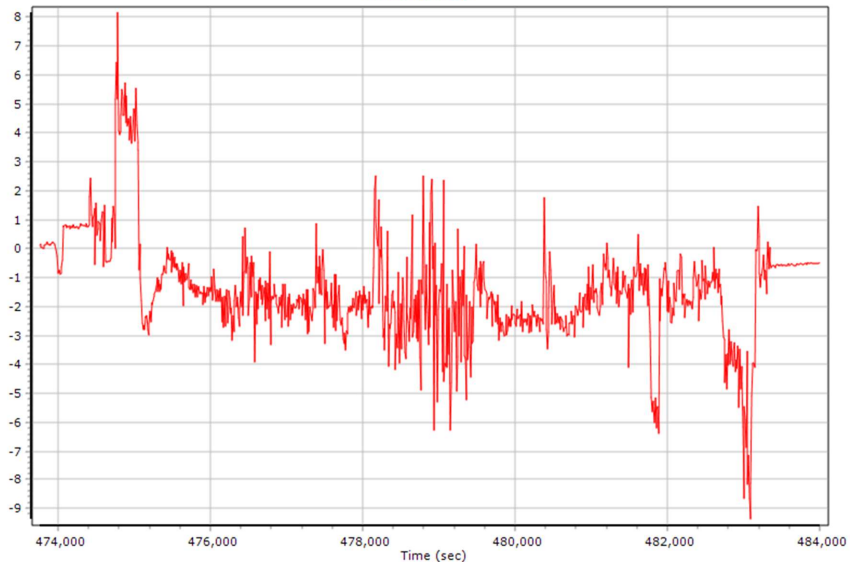
UTC Offset:

OK Cancel

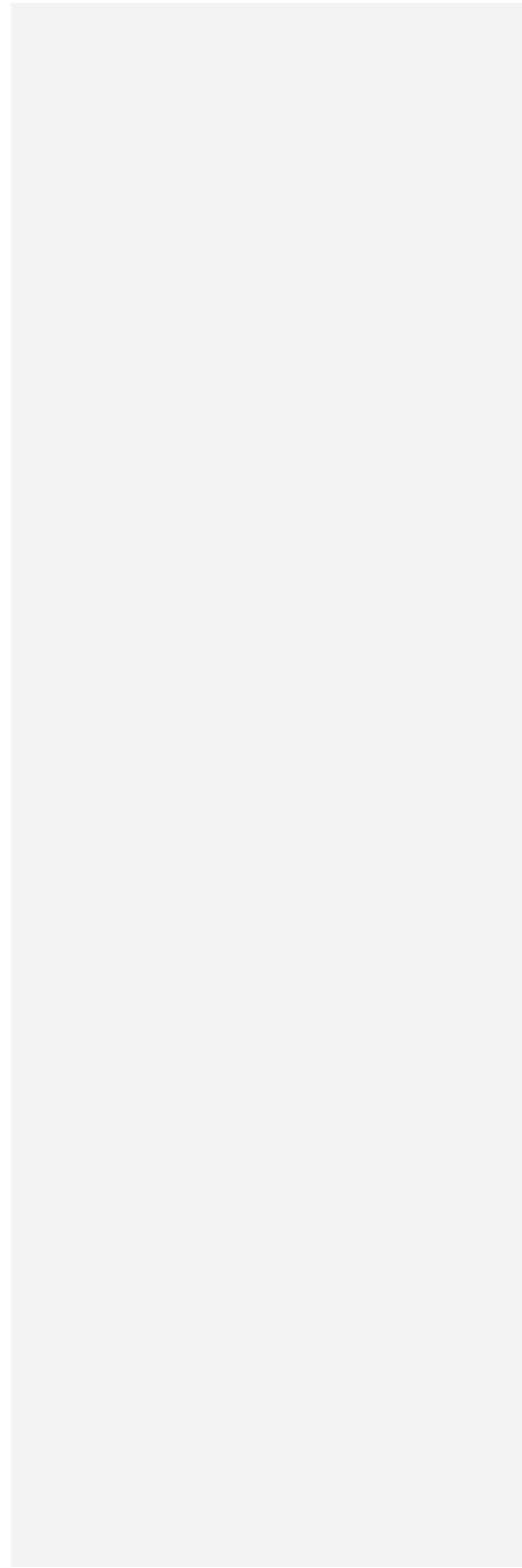
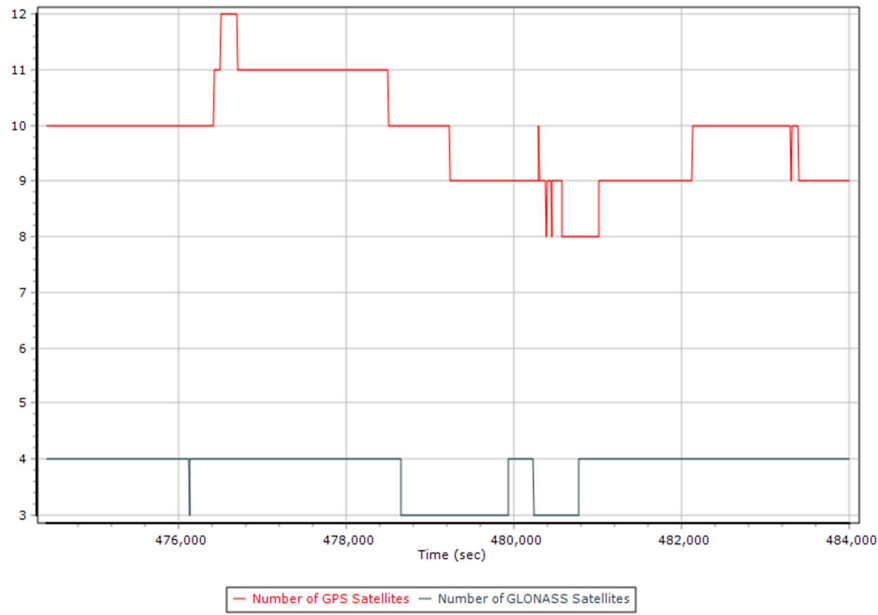


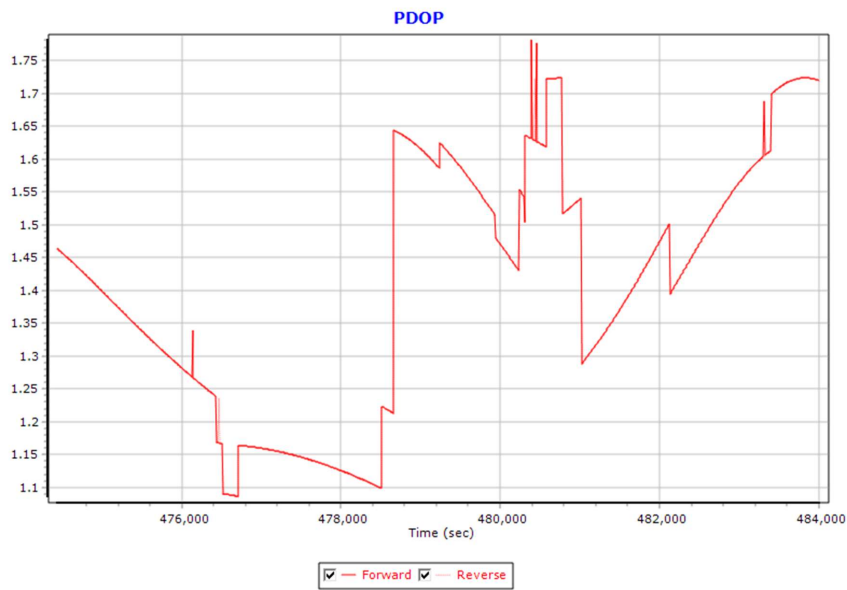
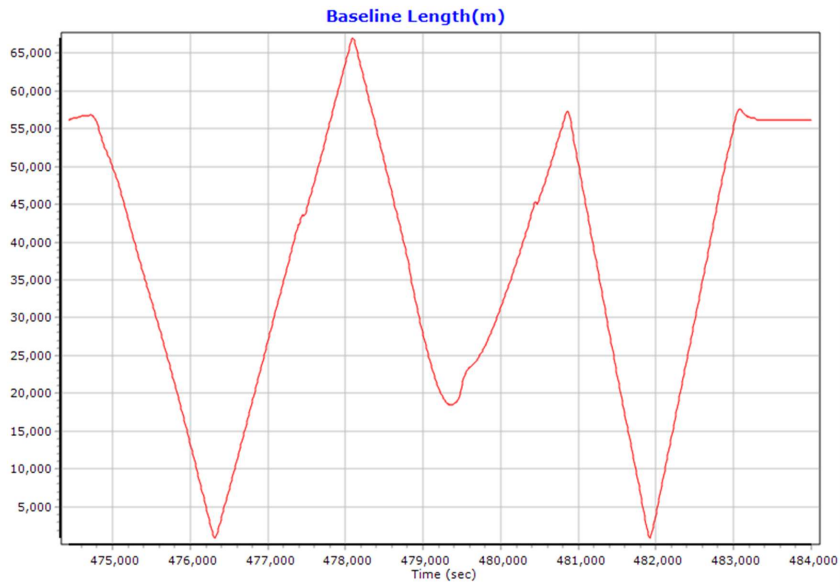


Pitch (deg)

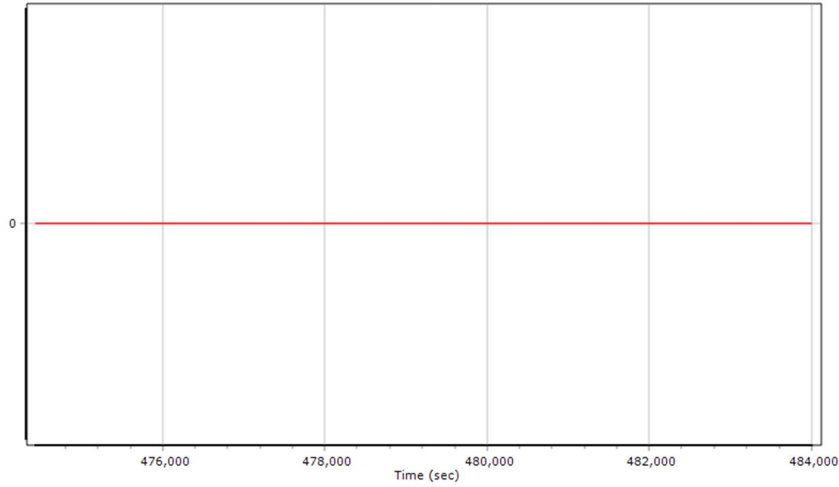


— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



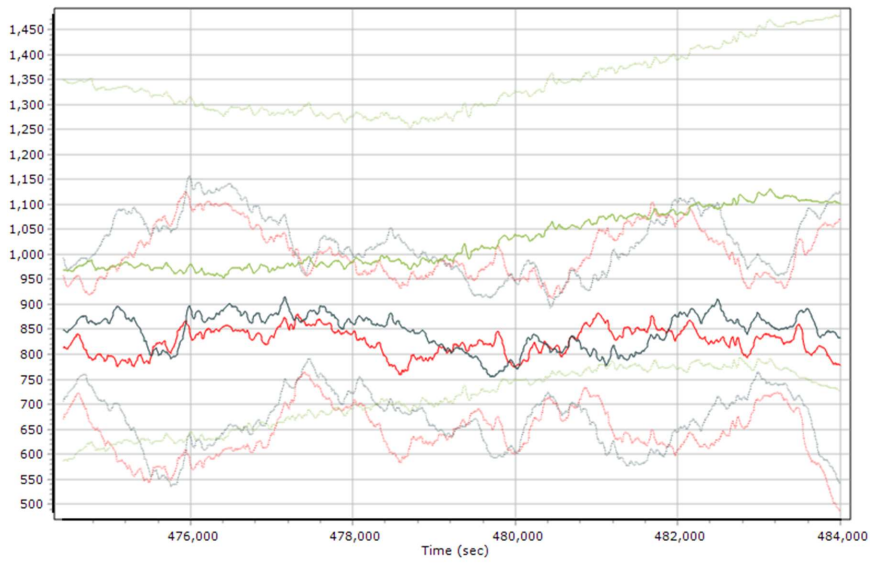


Processing Mode

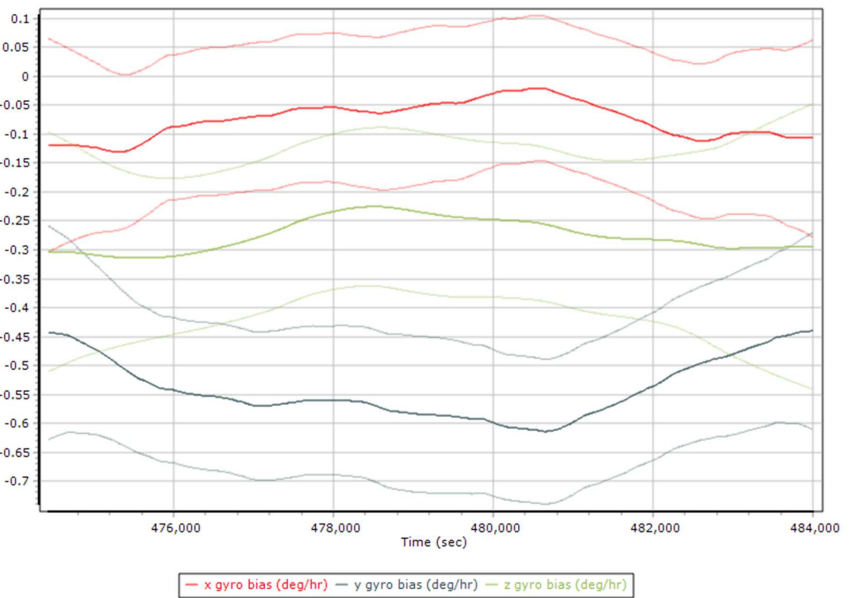
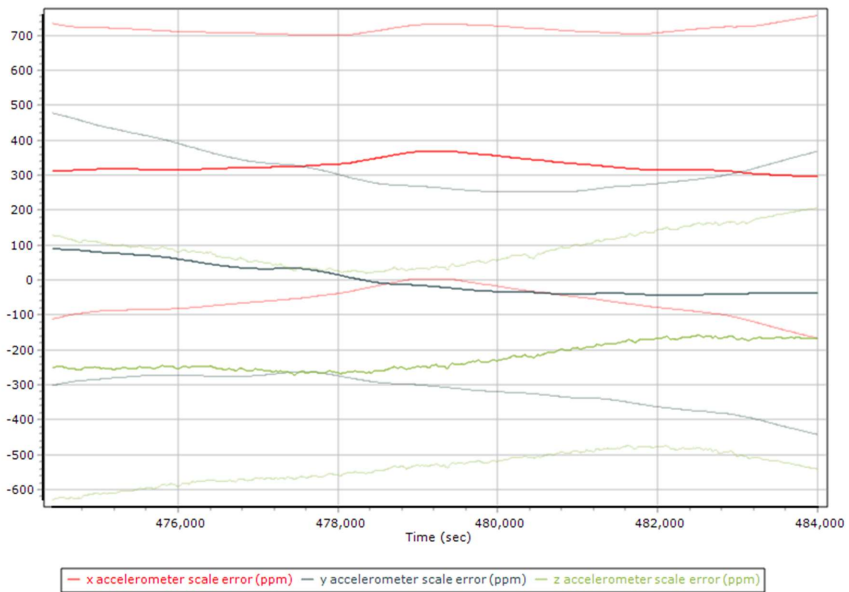


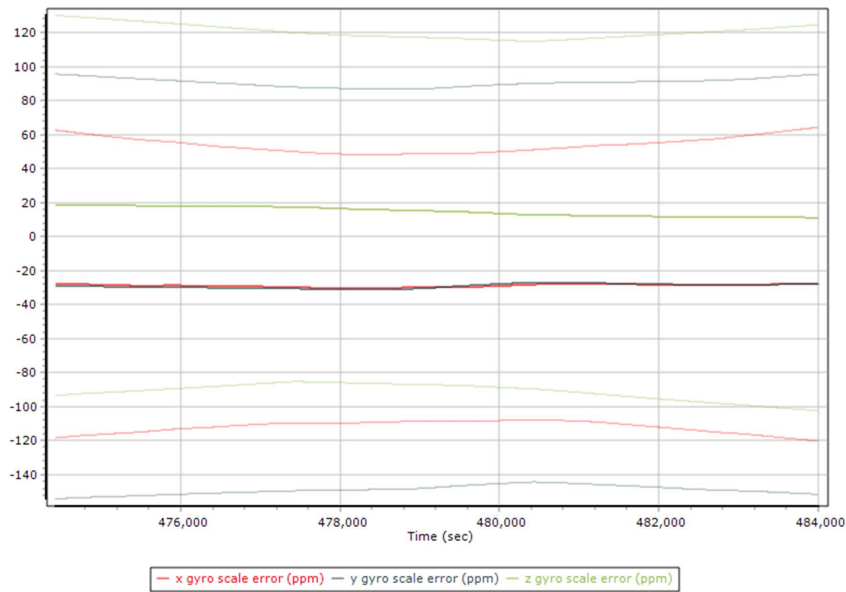
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

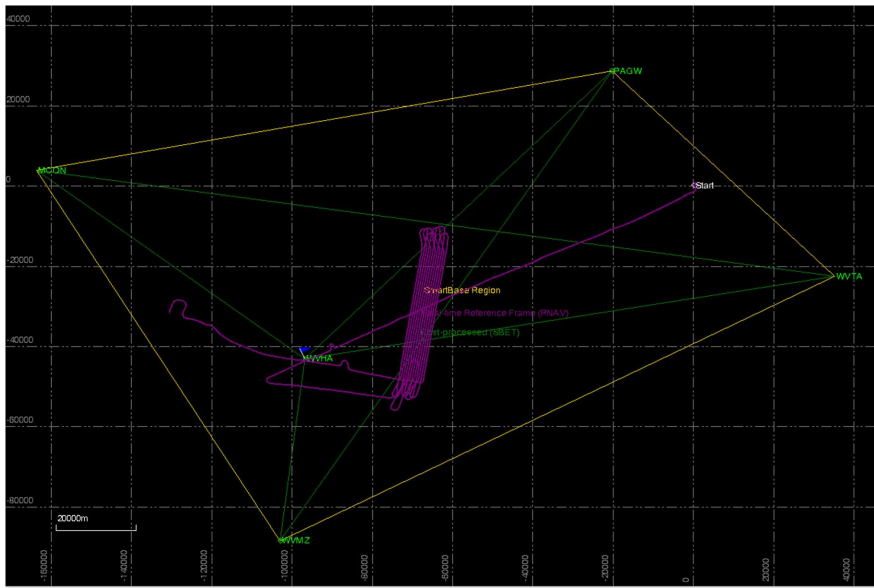


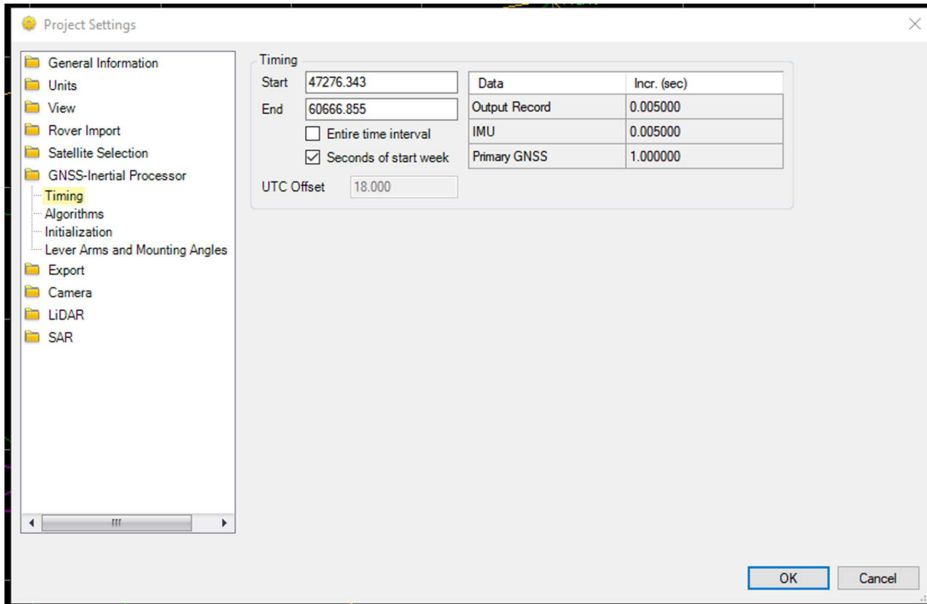
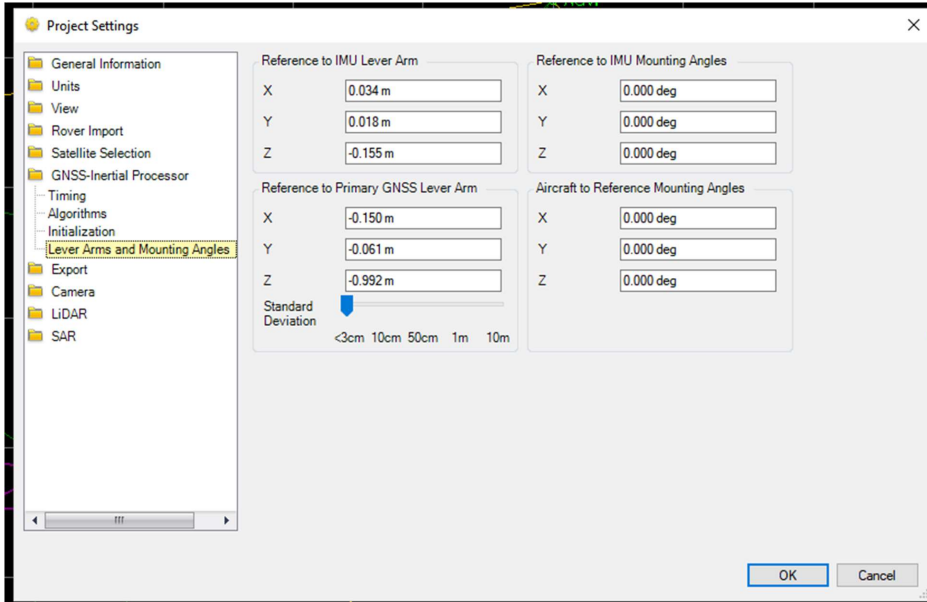
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)

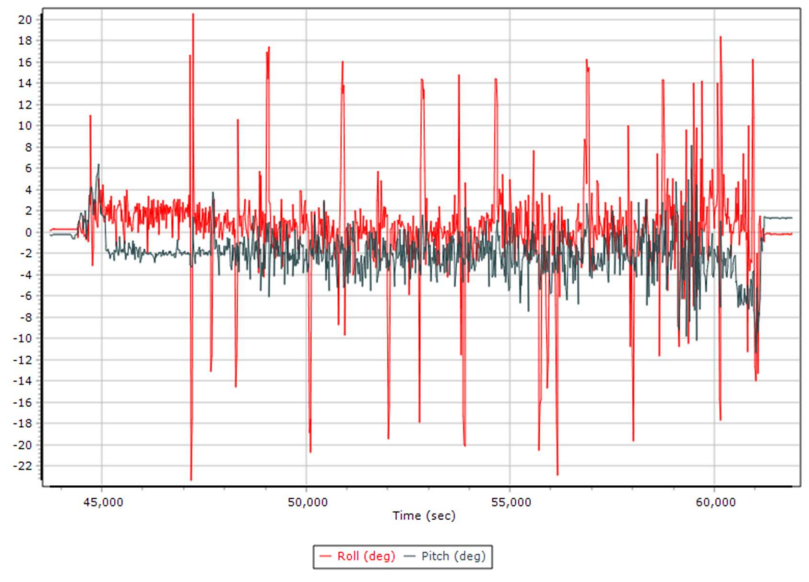
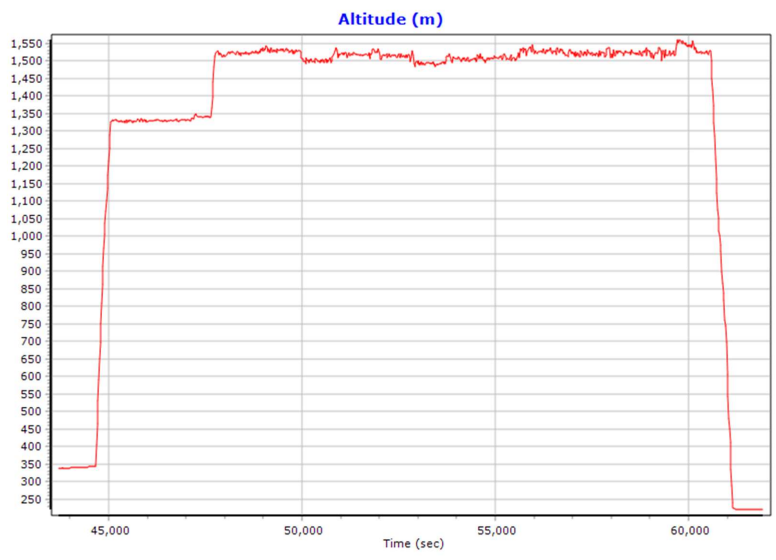


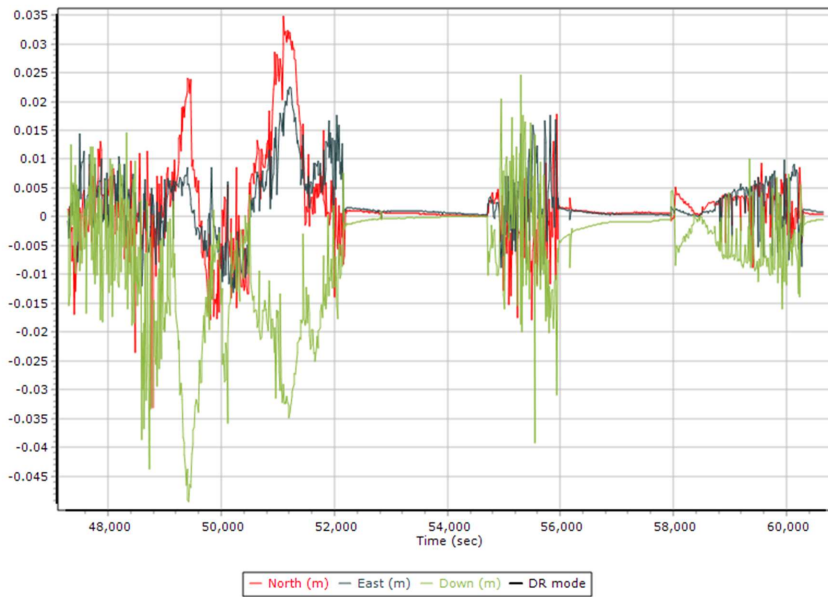
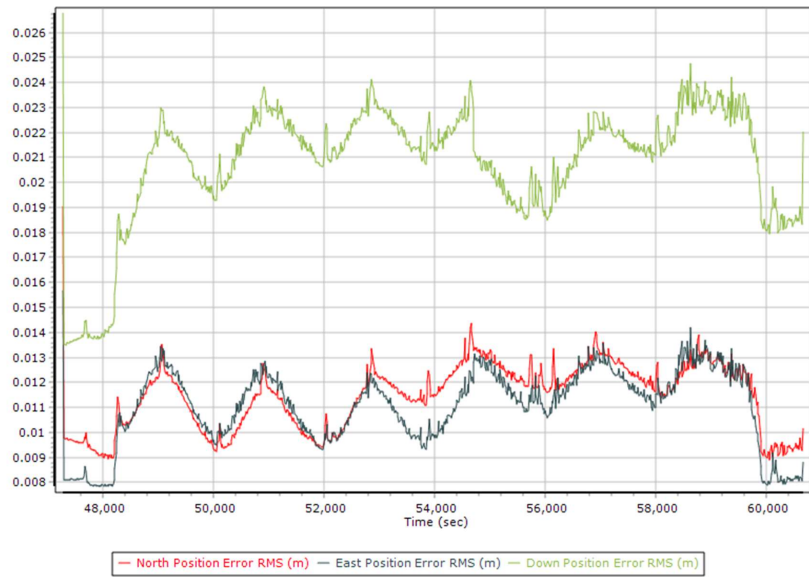


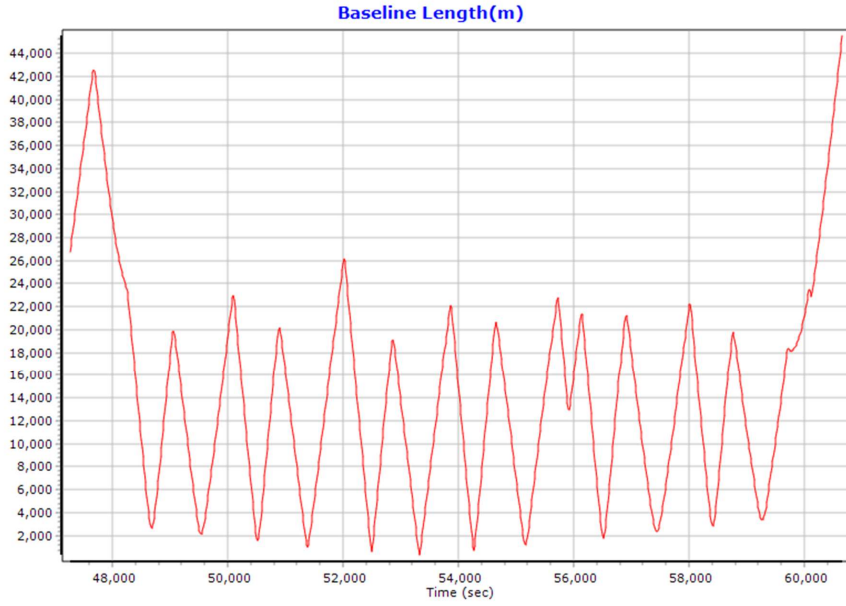
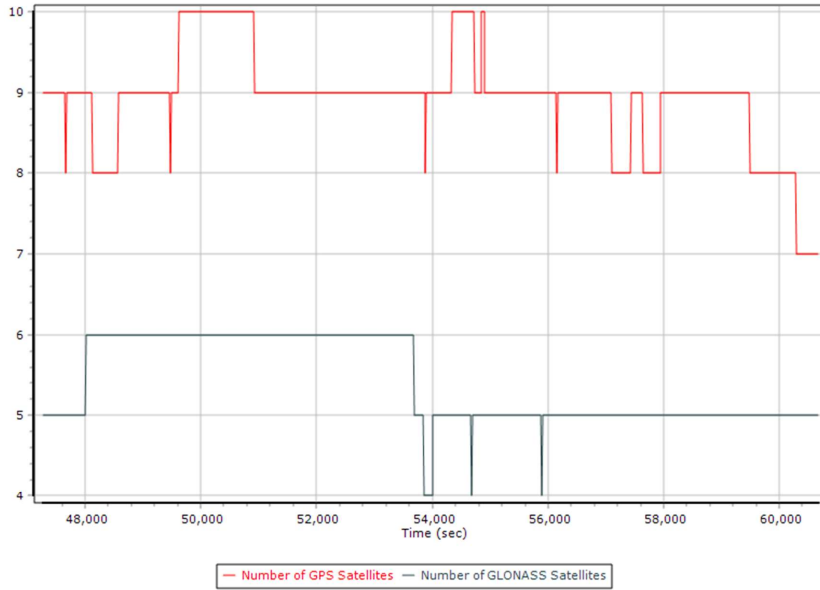
MNB19097A

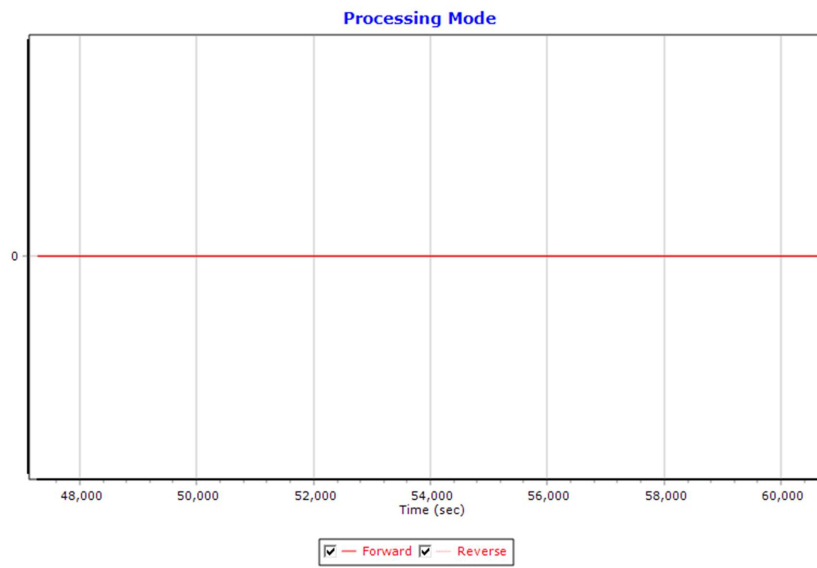
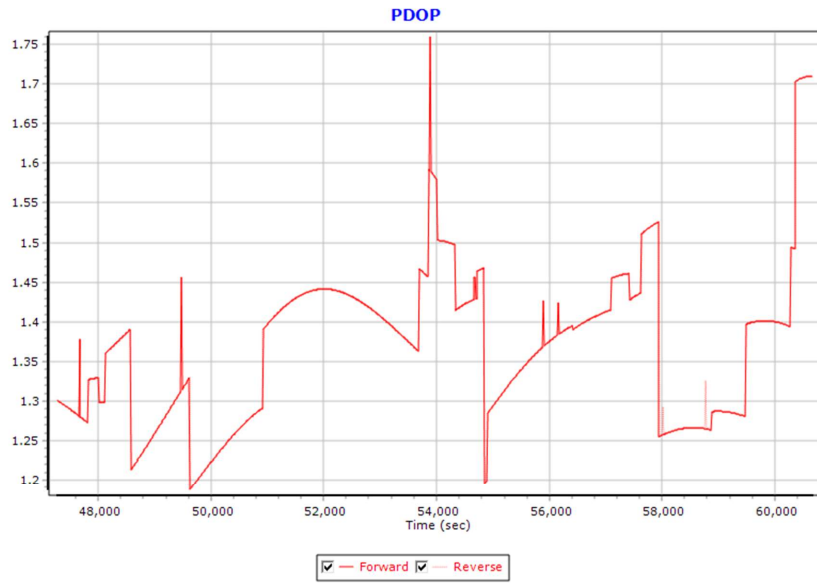




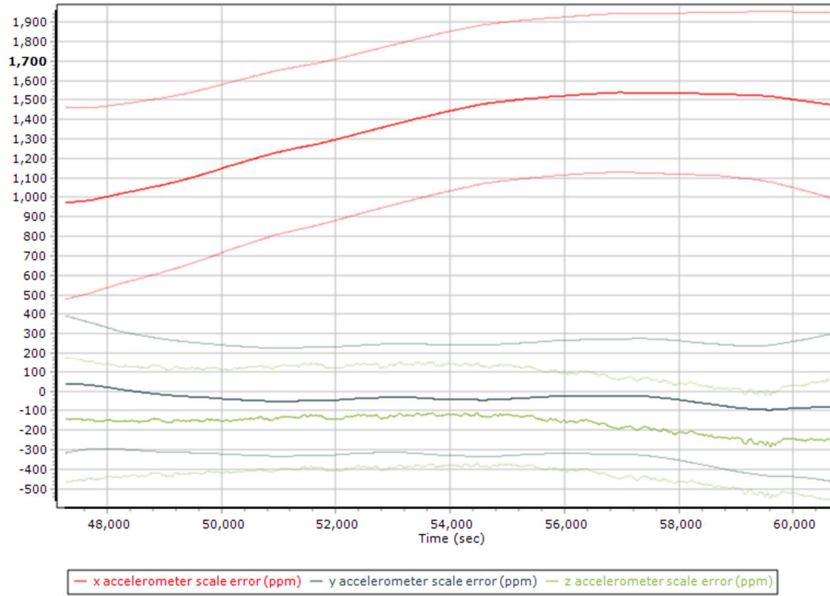
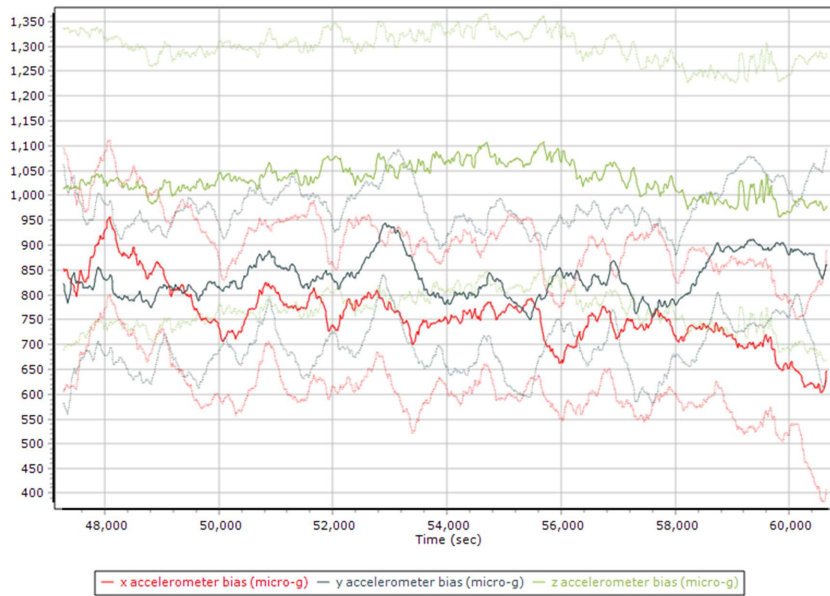


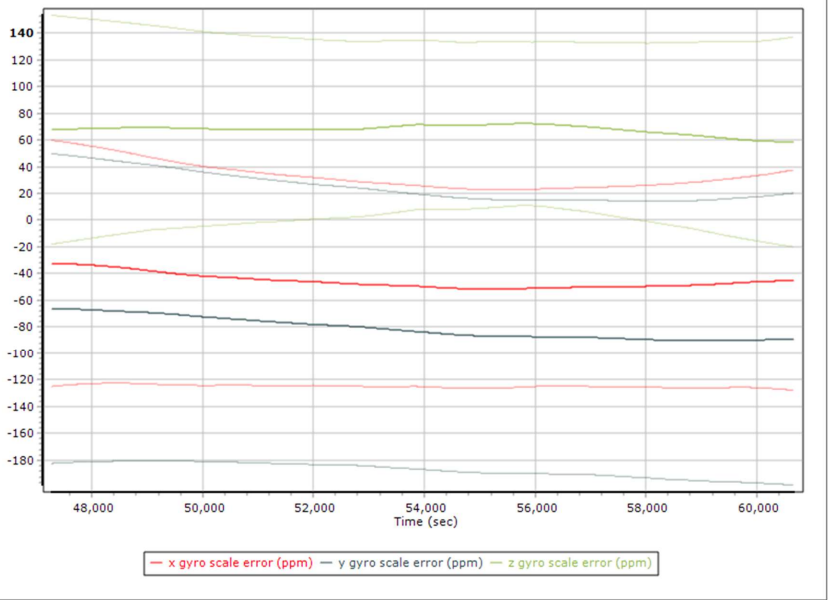
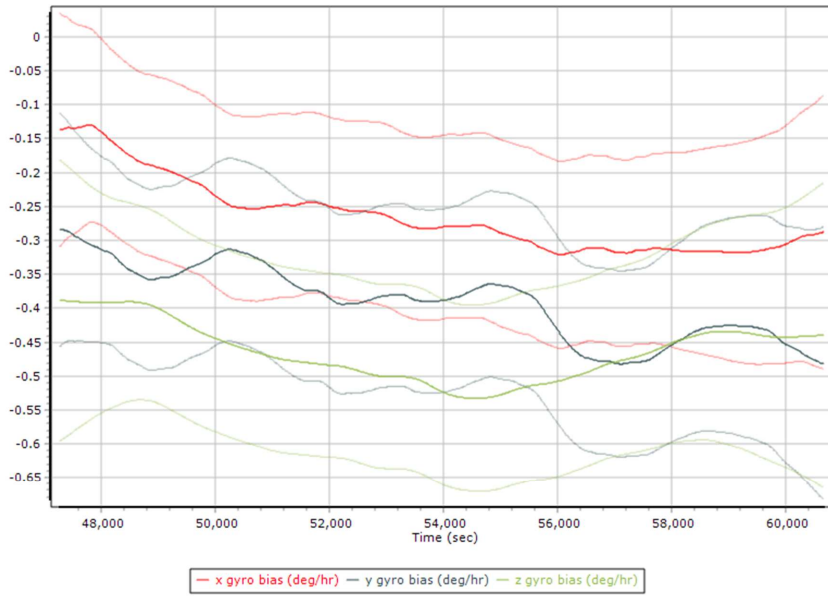




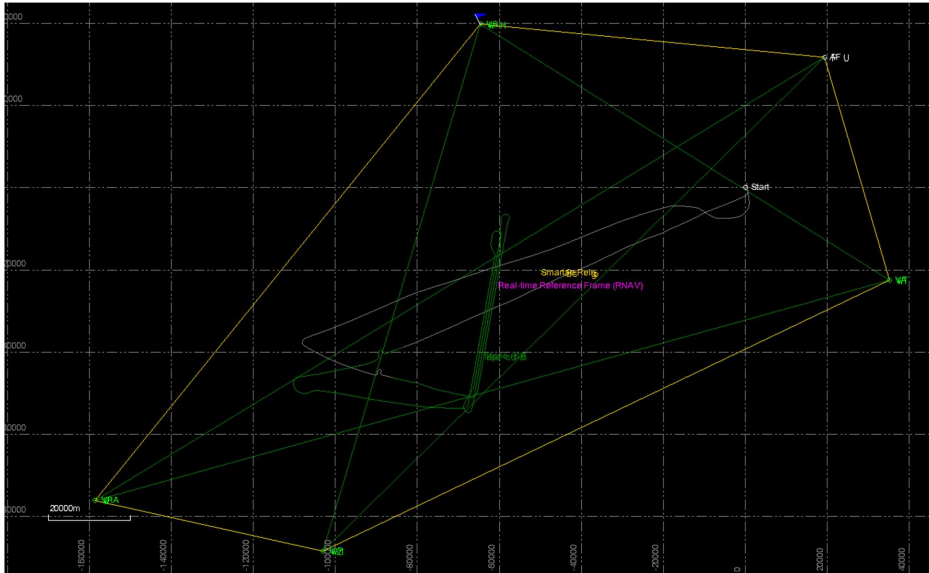


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR





MNB19100A



Reference to IMU Lever Arm

| | |
|---|---------------------------------------|
| X | <input type="text" value="0.034 m"/> |
| Y | <input type="text" value="0.018 m"/> |
| Z | <input type="text" value="-0.155 m"/> |

Reference to IMU Mounting Angles

| | |
|---|----------------------------------------|
| X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="0.000 deg"/> |

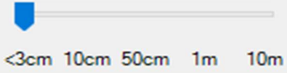
Reference to Primary GNSS Lever Arm

| | |
|---|---------------------------------------|
| X | <input type="text" value="-0.150 m"/> |
| Y | <input type="text" value="-0.061 m"/> |
| Z | <input type="text" value="-0.992 m"/> |

Aircraft to Reference Mounting Angles

| | |
|---|----------------------------------------|
| X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="0.000 deg"/> |

Standard Deviation



Timing

Start 306245.063

End 311979.259

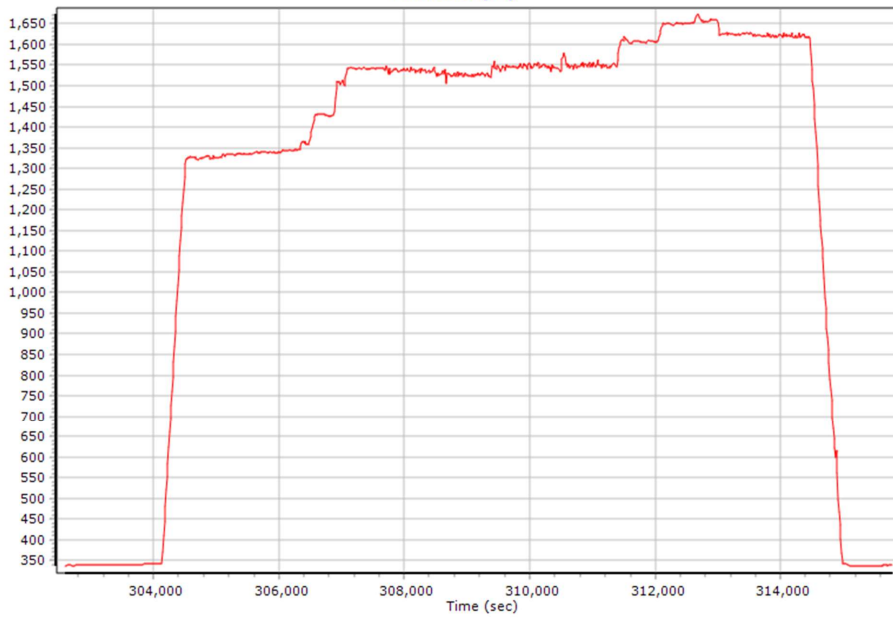
Entire time interval

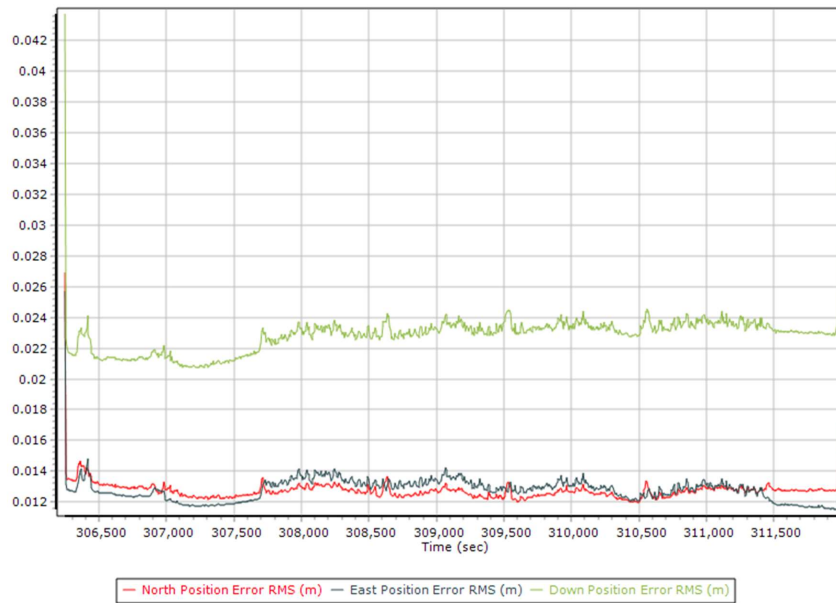
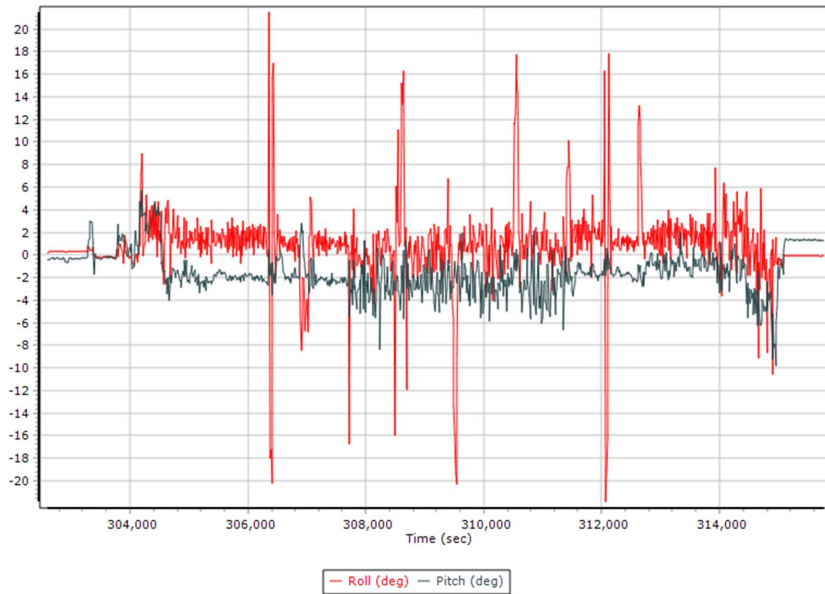
Seconds of start week

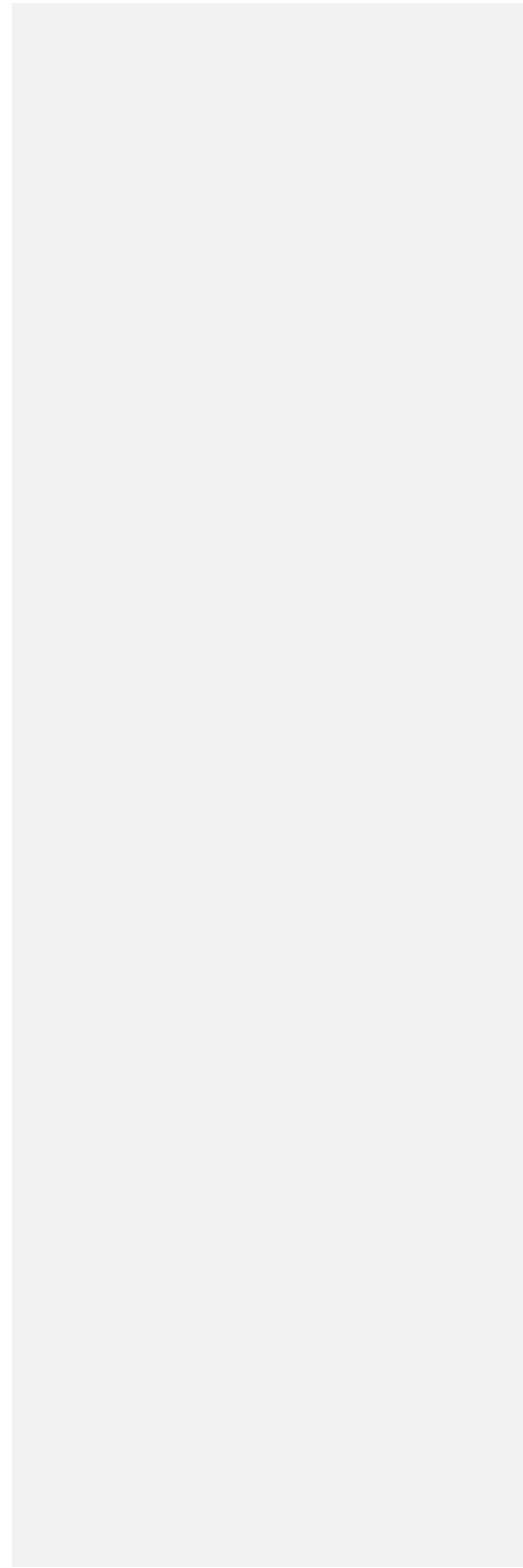
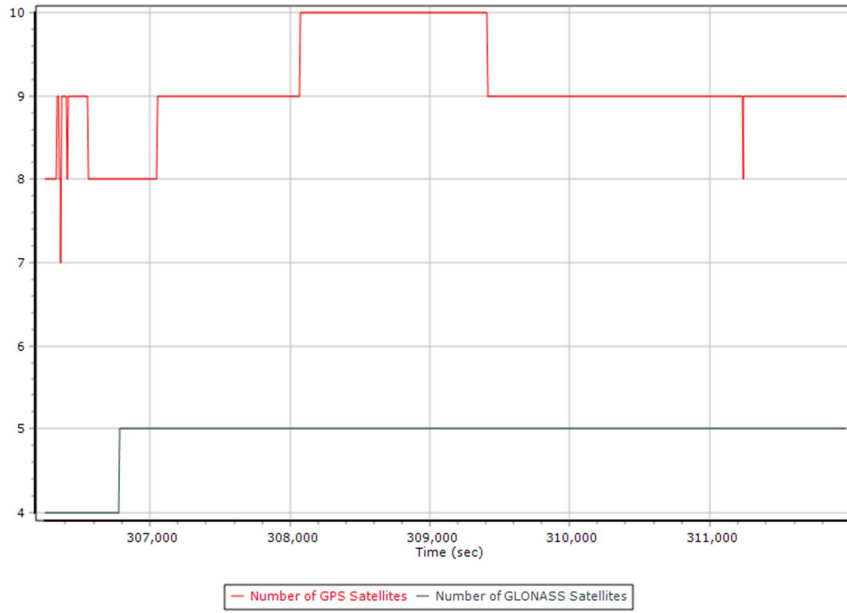
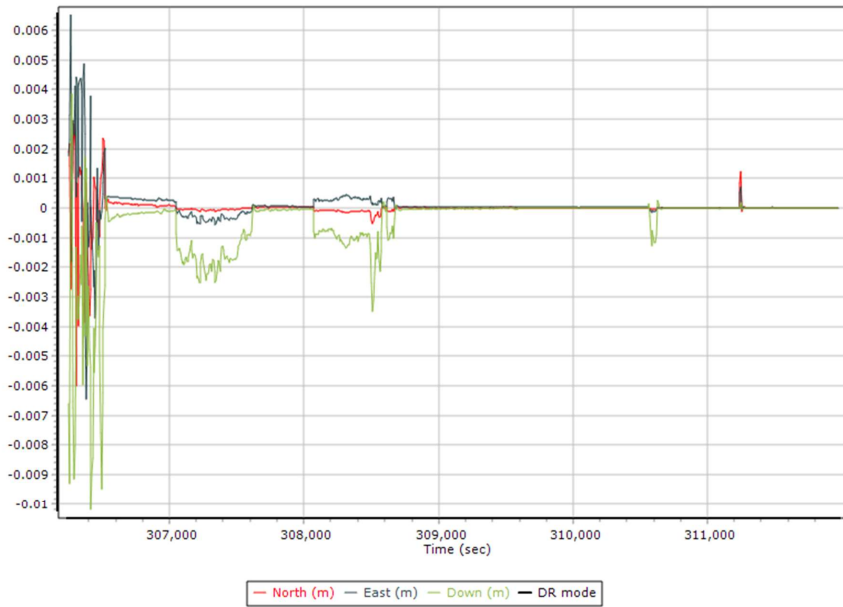
UTC Offset 18.000

| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

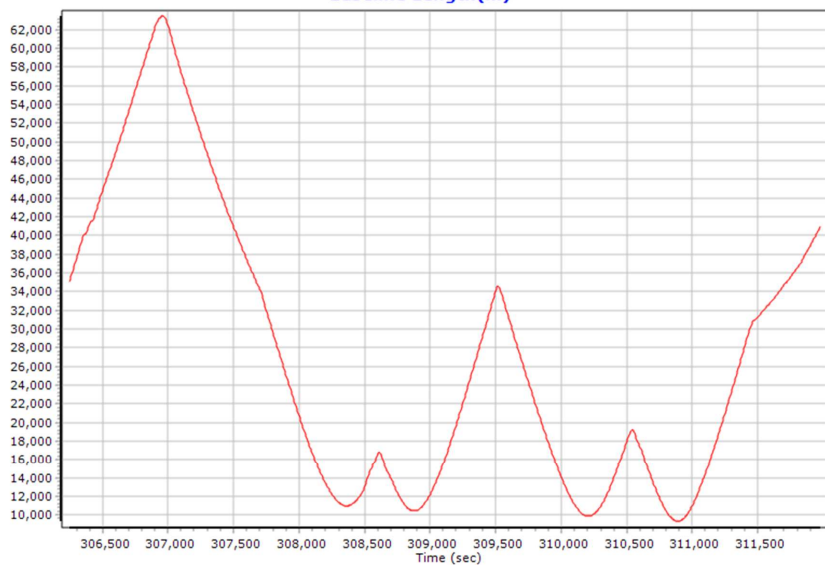
Altitude (m)



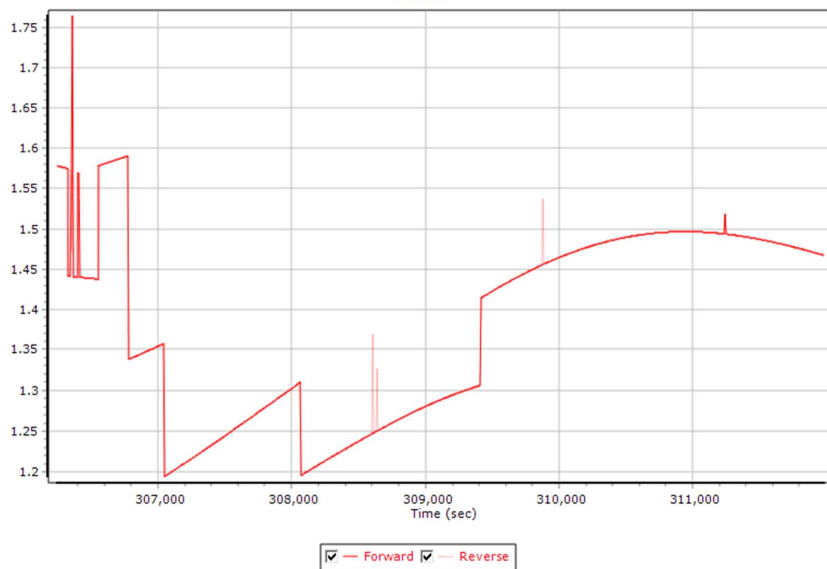




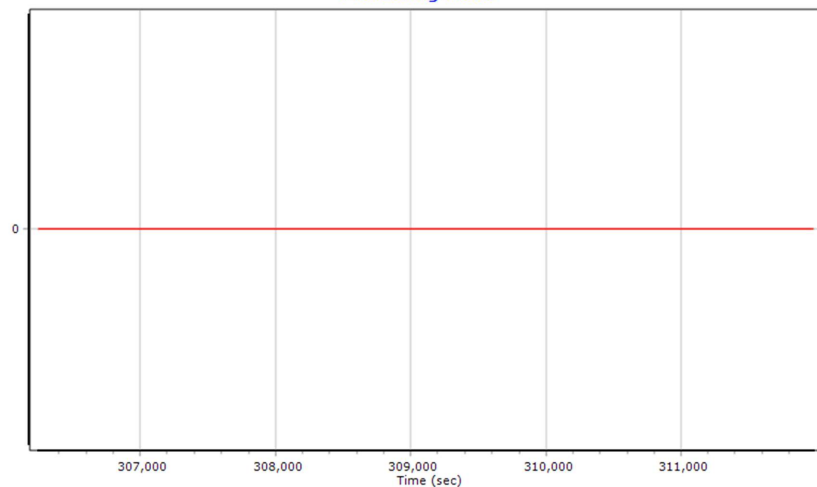
Baseline Length(m)



PDOP

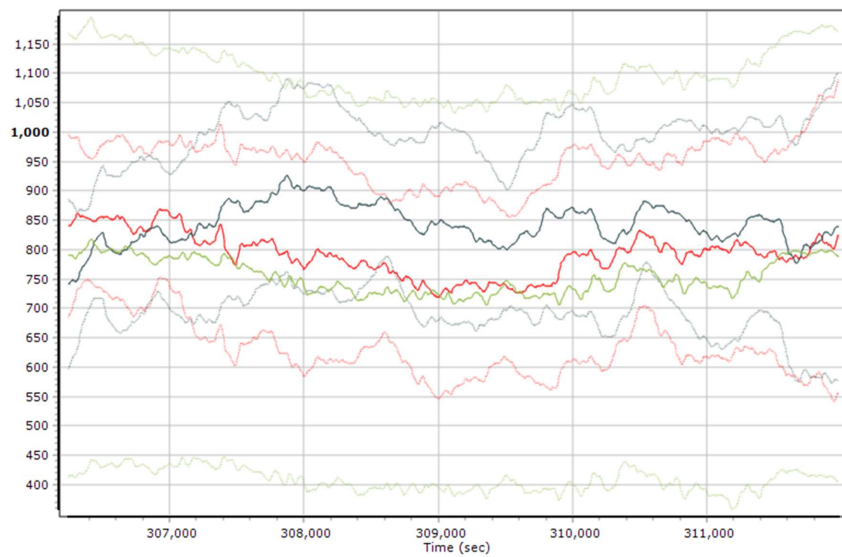


Processing Mode

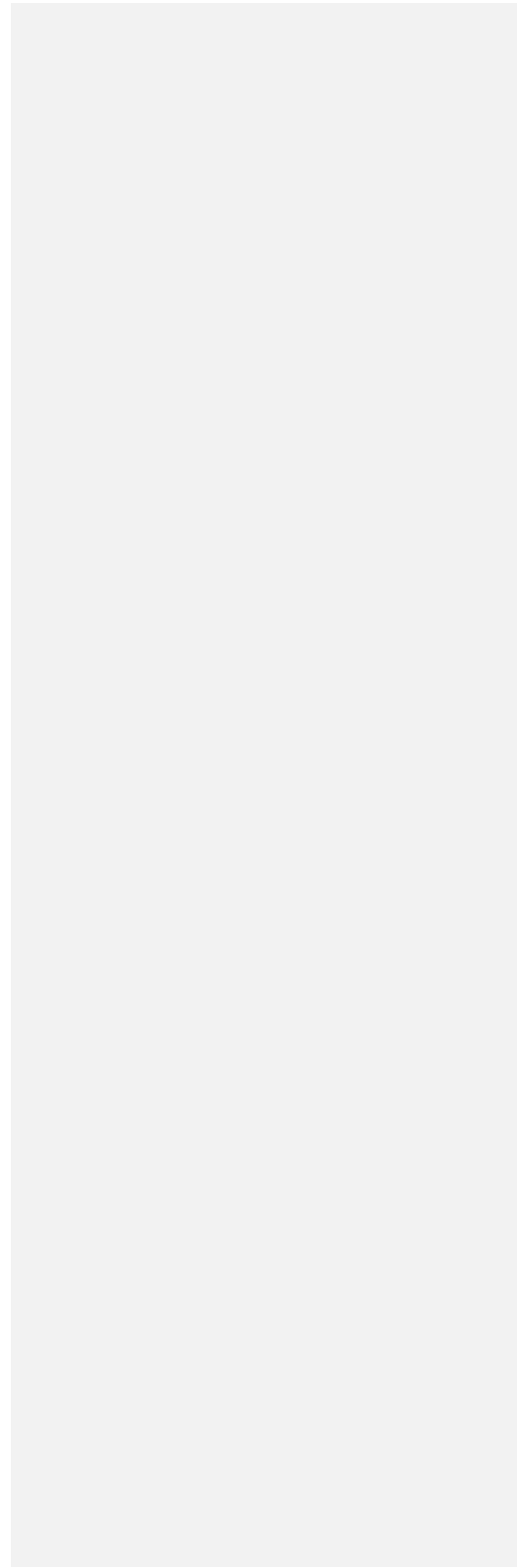
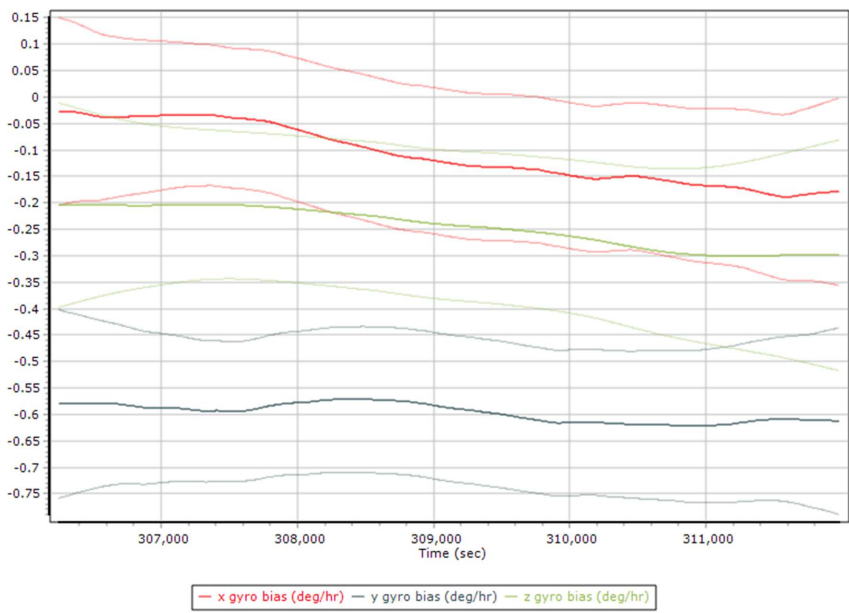
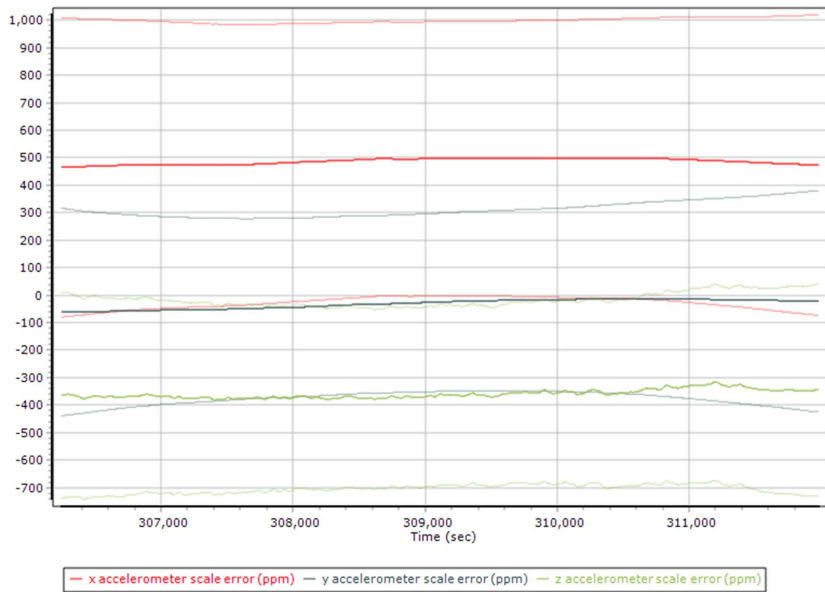


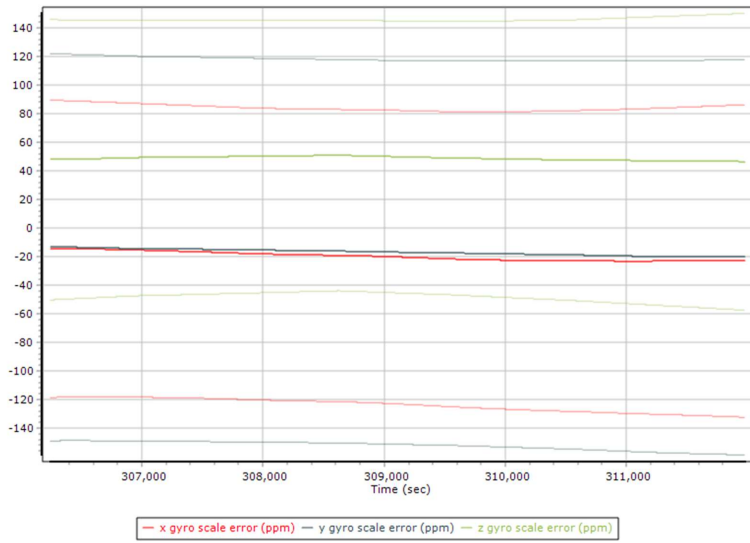
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

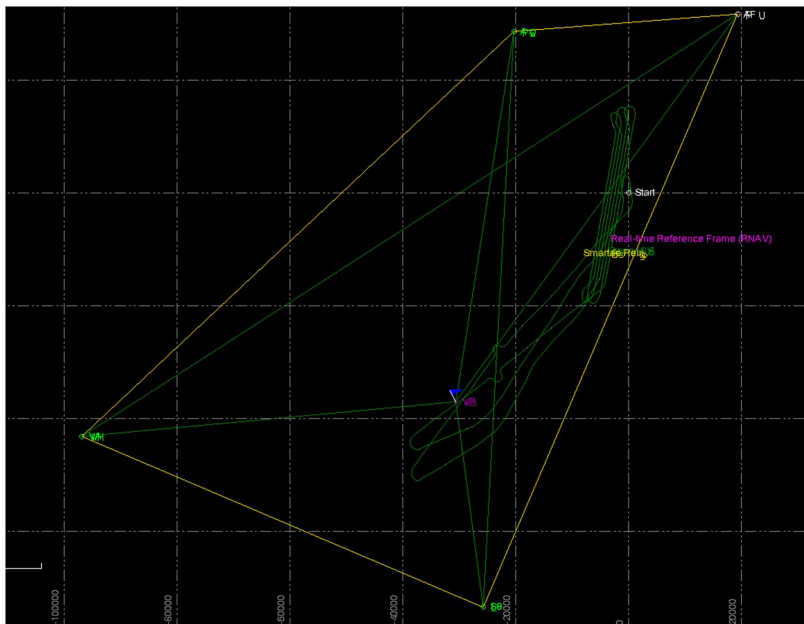


— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



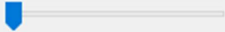


MNB190112A



| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
|----------------------------|---------------------------------------|----------------------------------|----------------------------------------|
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |

| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
|-------------------------------------|---------------------------------------|---------------------------------------|----------------------------------------|
| X | <input type="text" value="-0.150 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.061 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.099 m"/> | Z | <input type="text" value="0.000 deg"/> |

Standard Deviation 

<3cm 10cm 50cm 1m 10m

Timing

Start

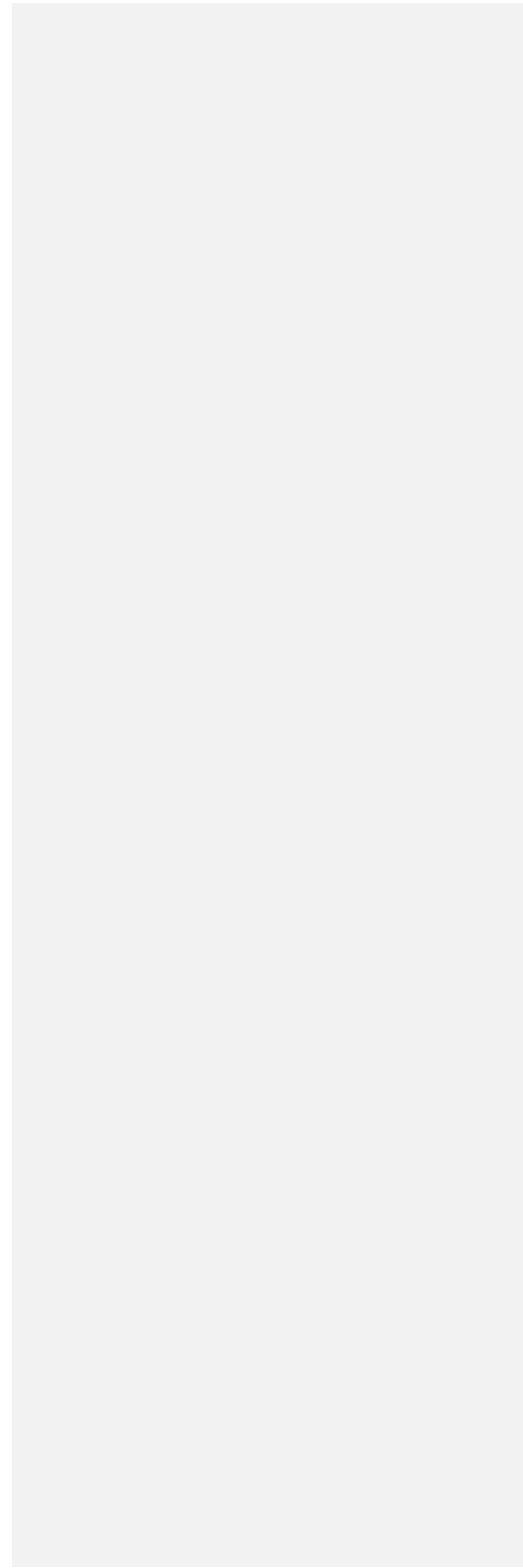
End

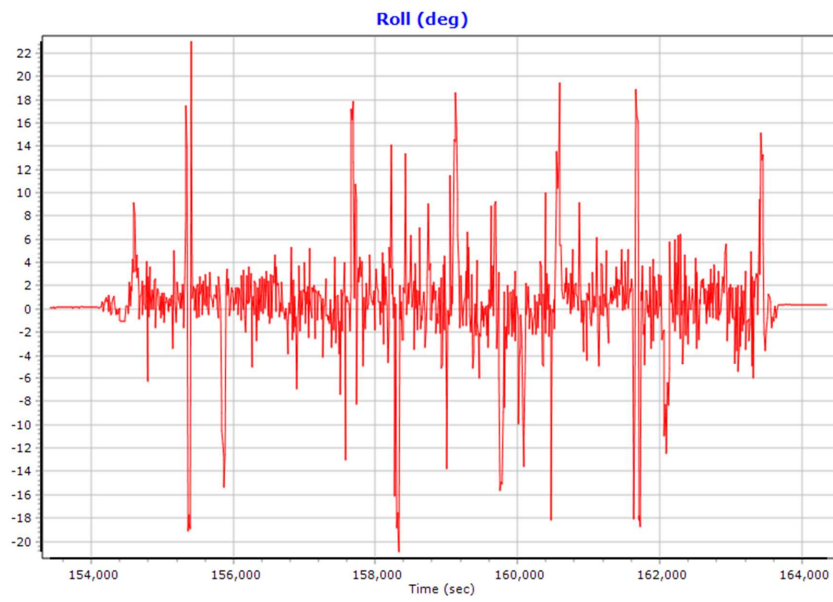
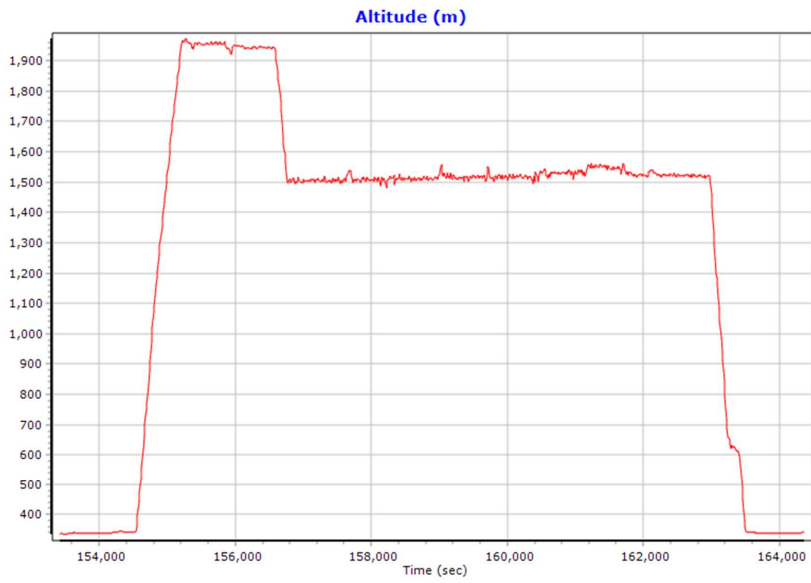
Entire time interval

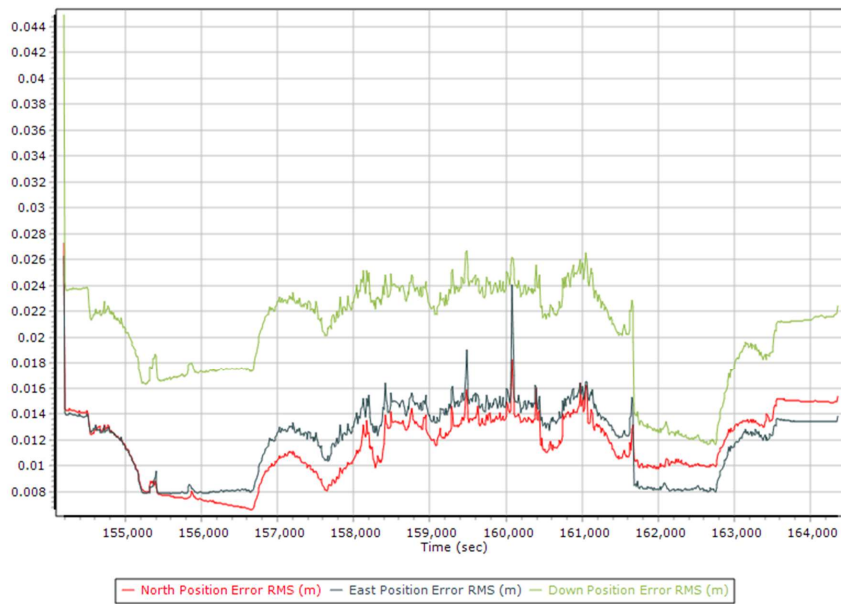
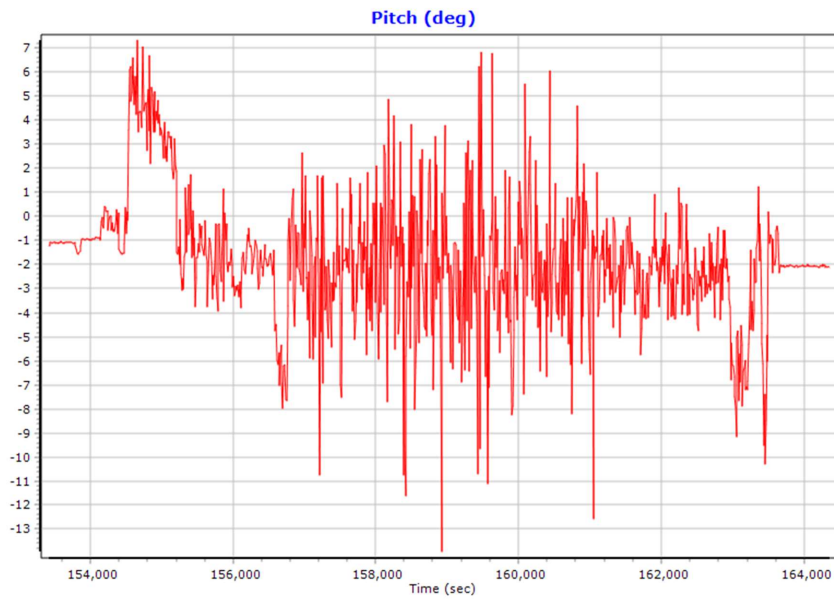
Seconds of start week

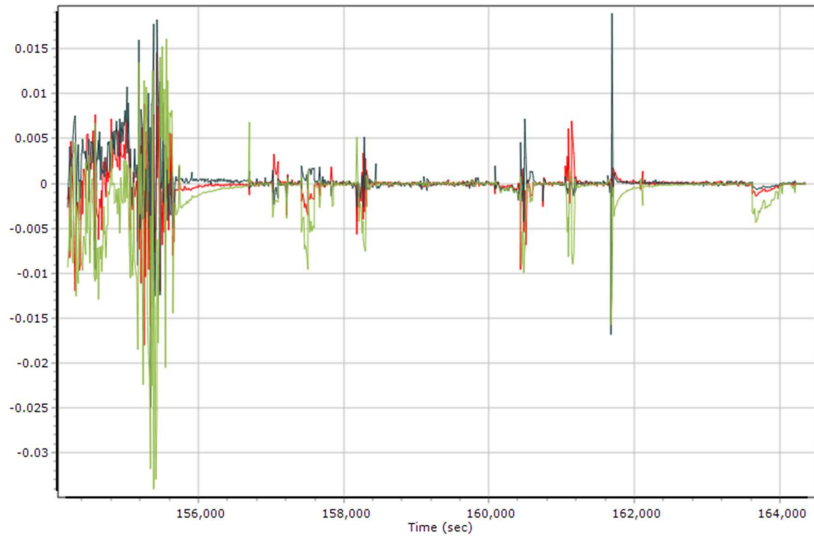
UTC Offset

| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

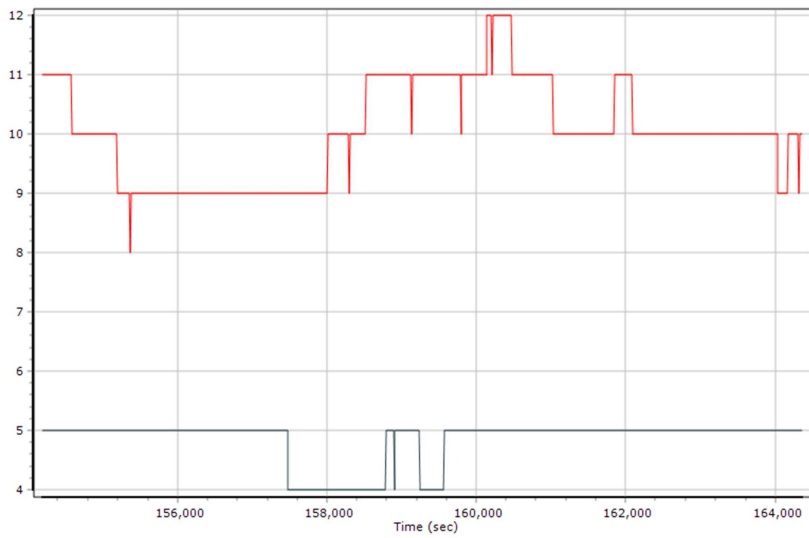




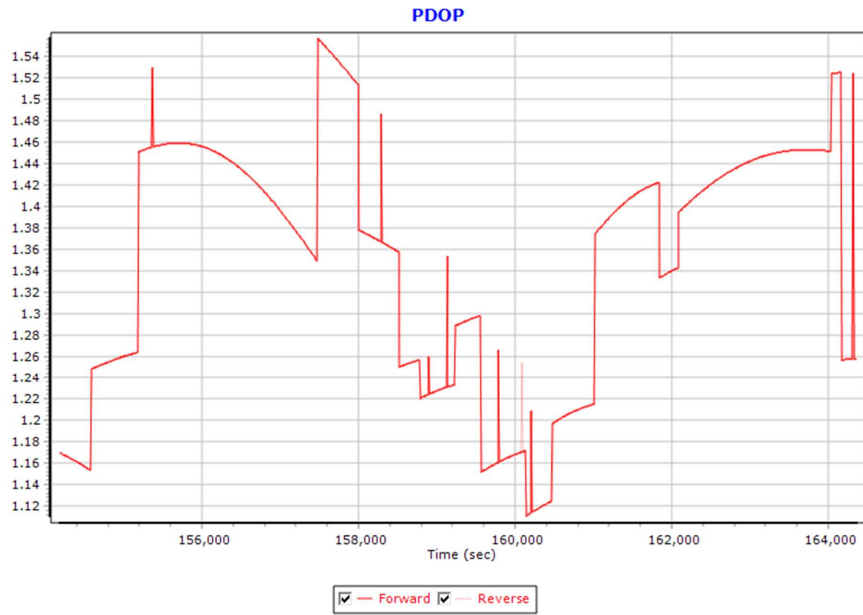
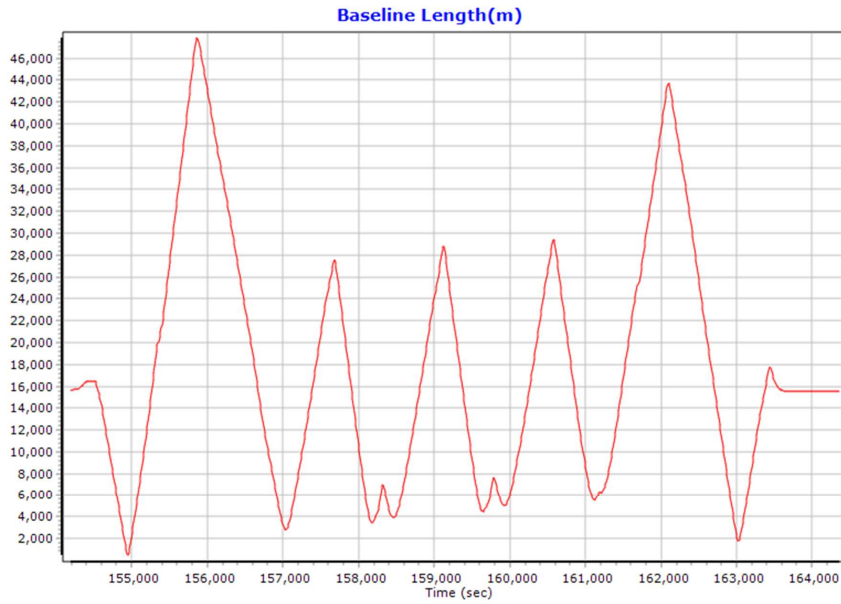




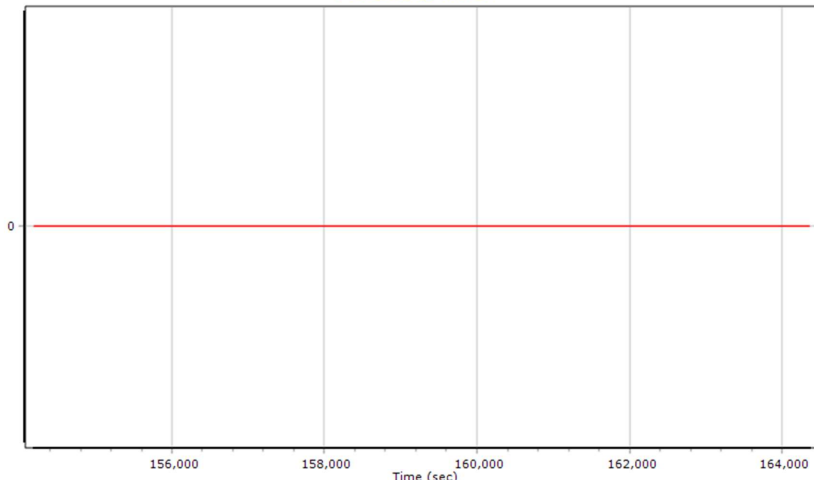
— North (m) — East (m) — Down (m) — DR mode



— Number of GPS Satellites — Number of GLONASS Satellites

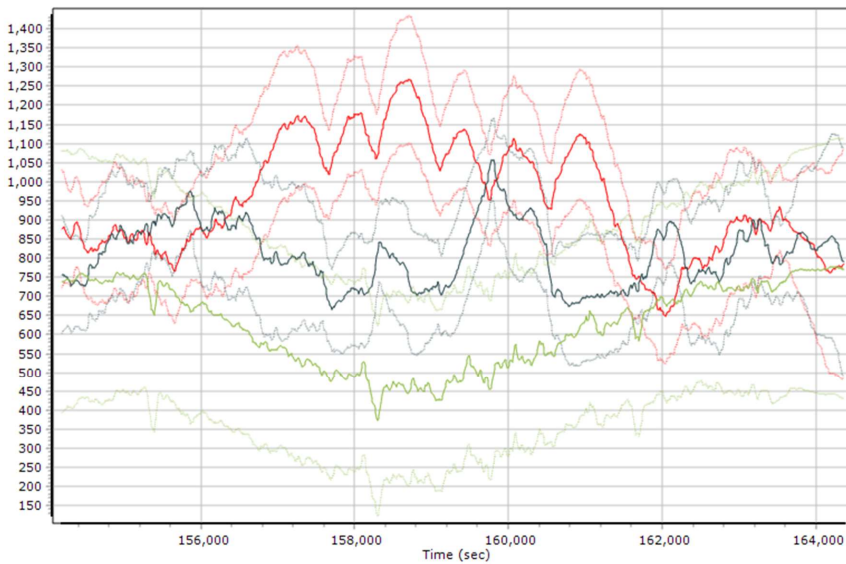


Processing Mode

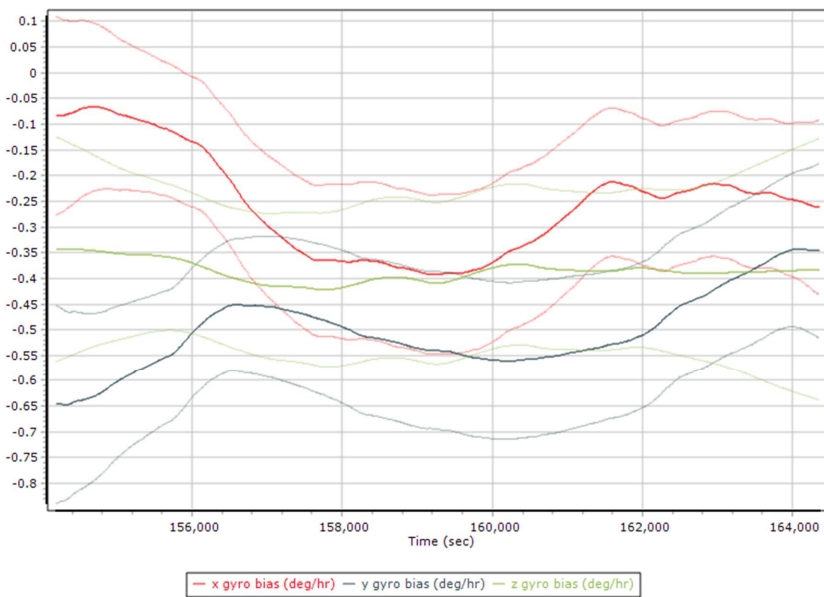
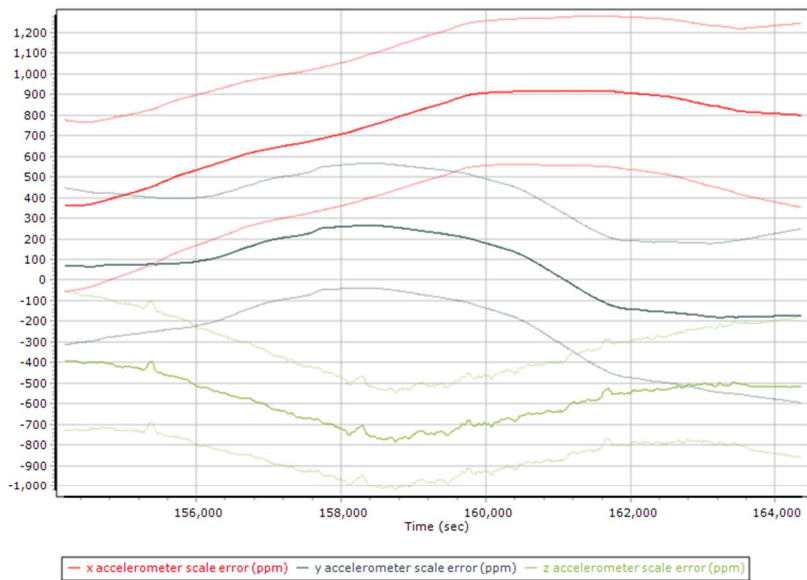


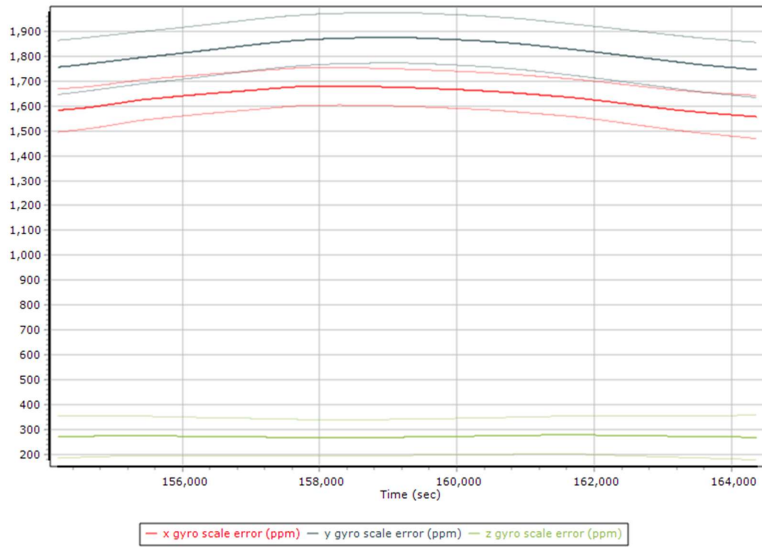
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

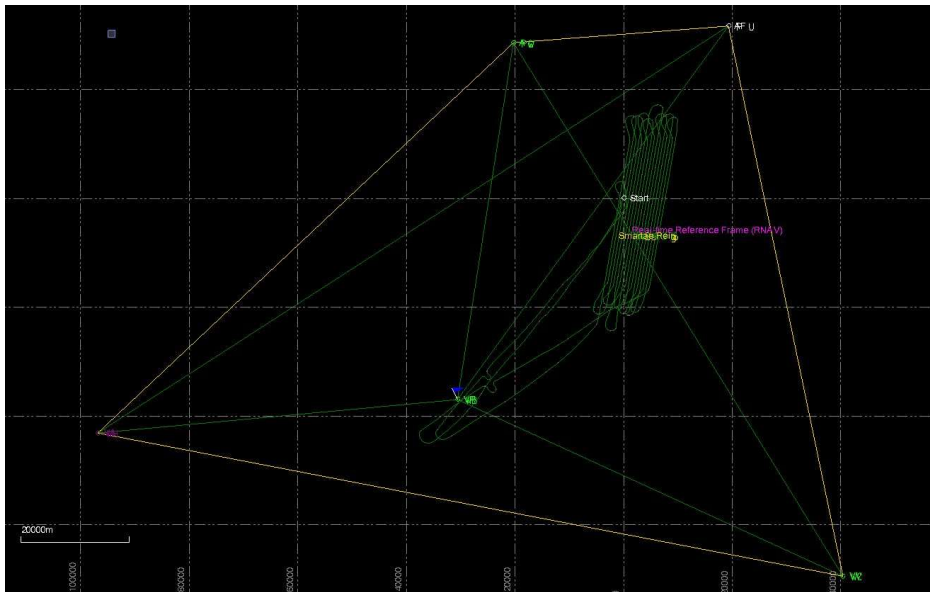


— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)






MNB190113A



| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
|----------------------------|----------|----------------------------------|-----------|
| X | 0.034 m | X | 0.000 deg |
| Y | 0.018 m | Y | 0.000 deg |
| Z | -0.155 m | Z | 0.000 deg |

| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
|-------------------------------------|----------|---------------------------------------|-----------|
| X | -0.150 m | X | 0.000 deg |
| Y | -0.061 m | Y | 0.000 deg |
| Z | -0.992 m | Z | 0.000 deg |

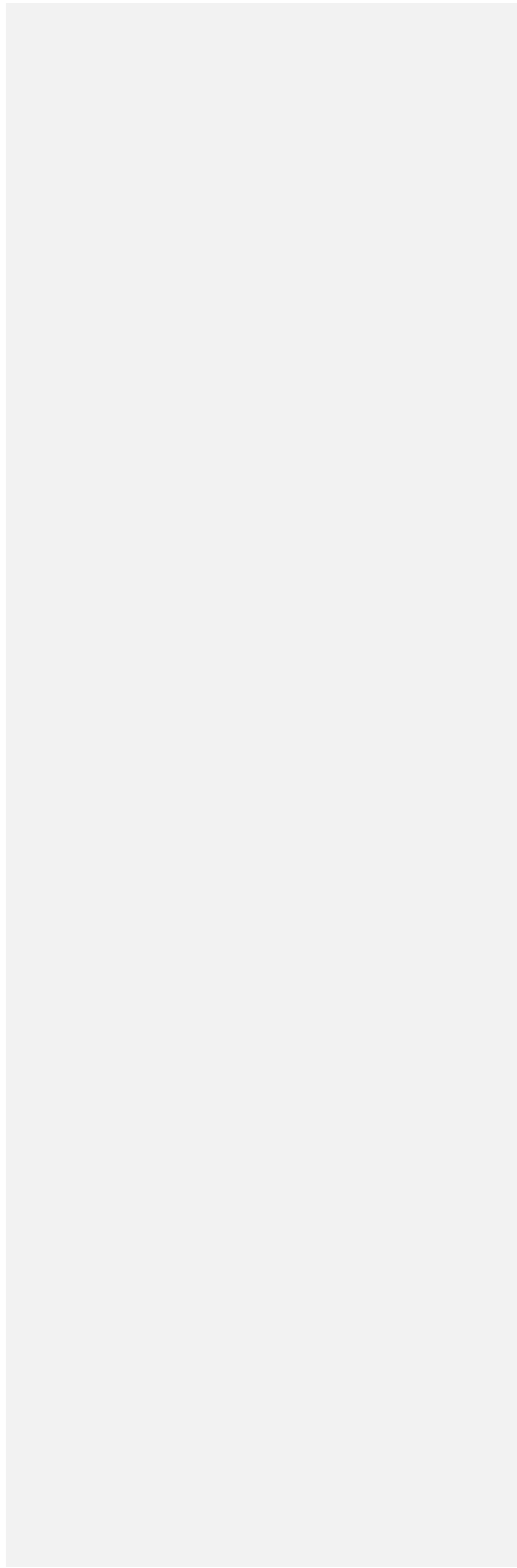
Standard Deviation 

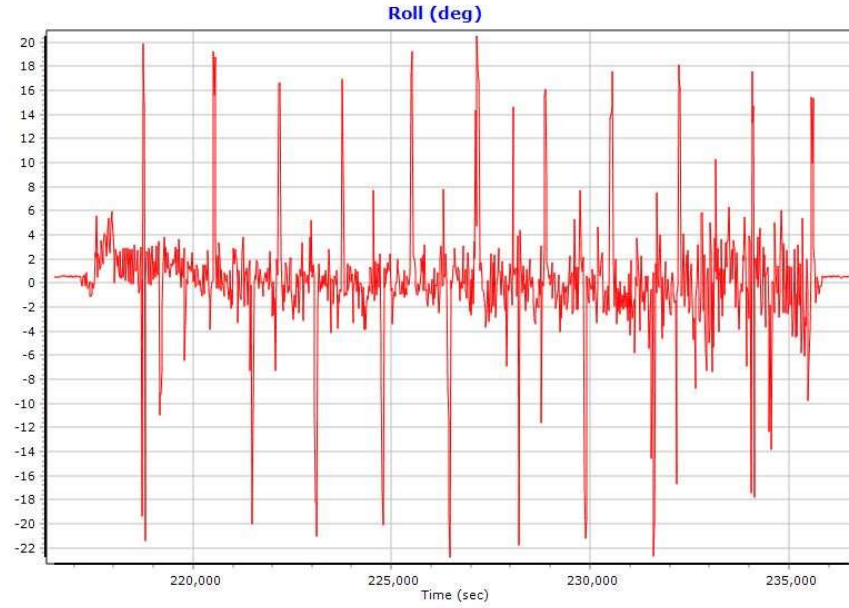
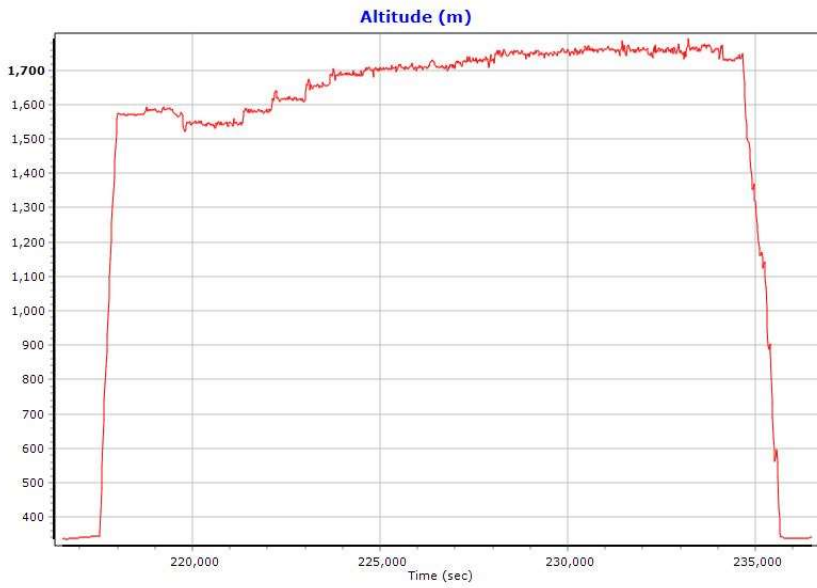
<3cm 10cm 50cm 1m 10m

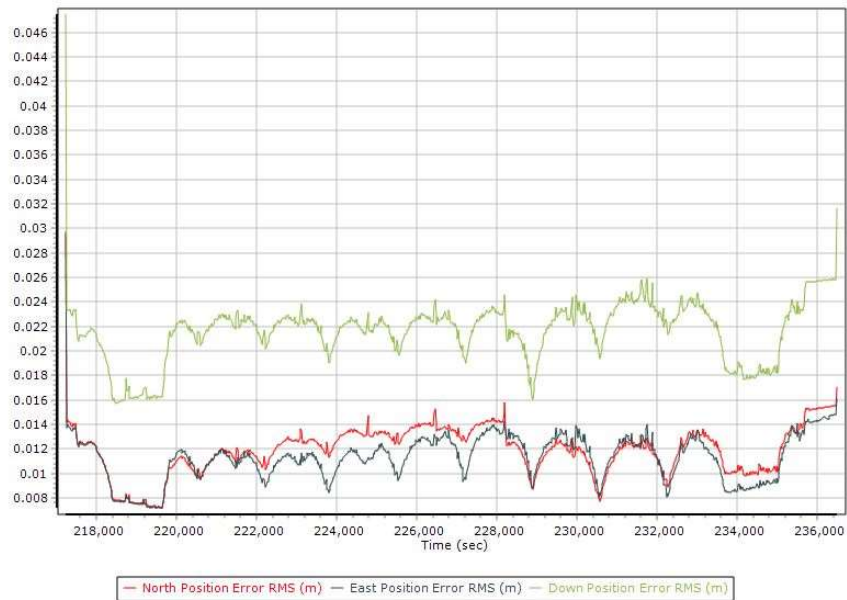
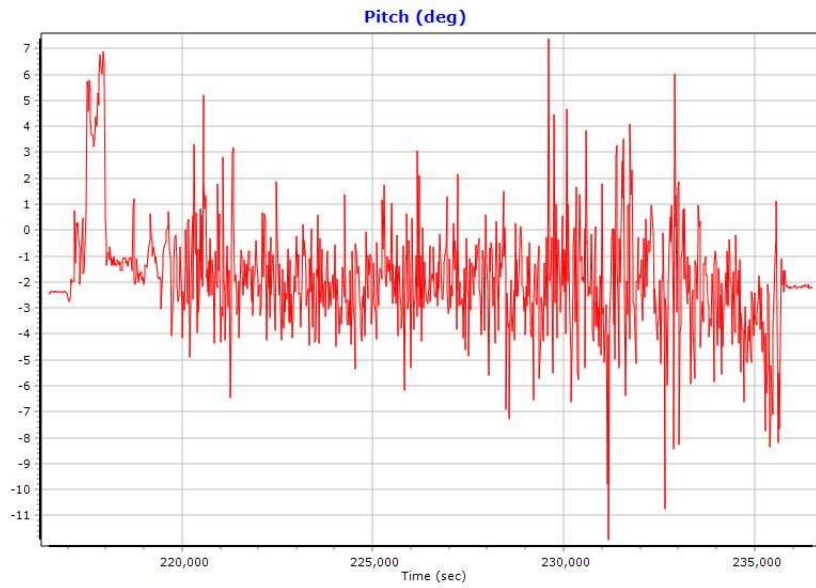
Timing

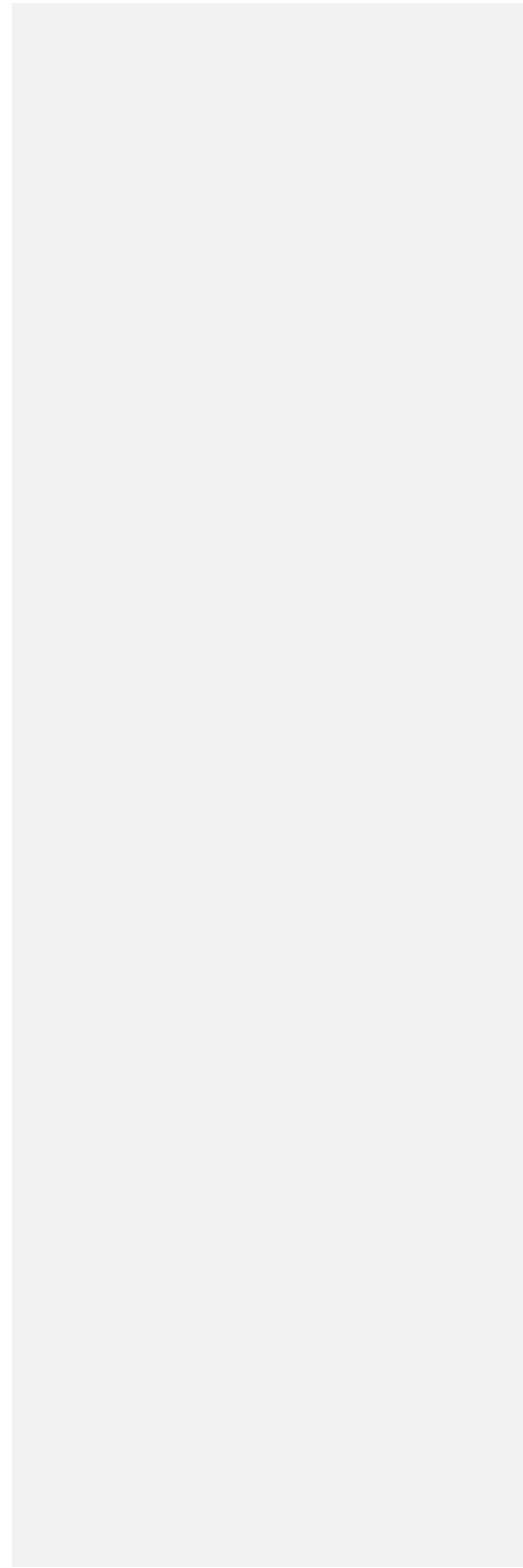
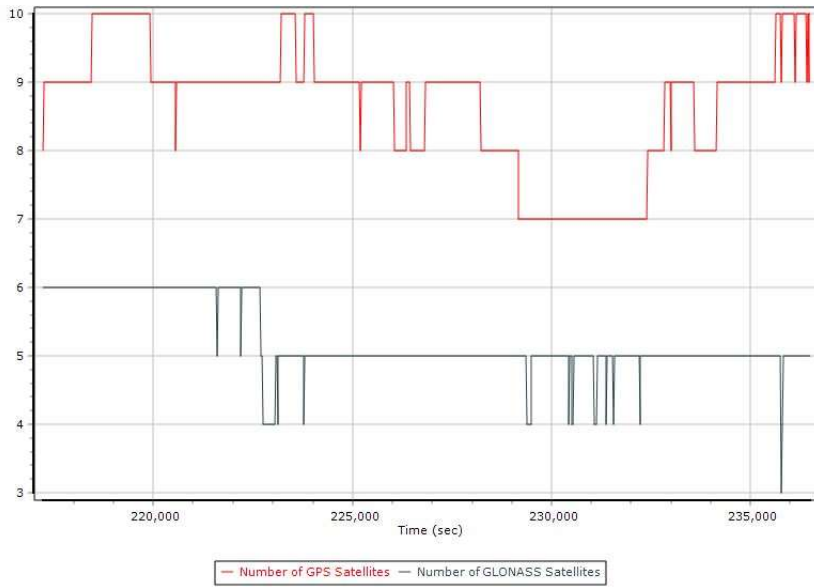
| | | | |
|-----------------------------------------------------------|------------|---------------|-------------|
| Start | 216520.000 | Data | Incr. (sec) |
| End | 236504.000 | Output Record | 0.005000 |
| <input checked="" type="checkbox"/> Entire time interval | | IMU | 0.005000 |
| <input checked="" type="checkbox"/> Seconds of start week | | Primary GNSS | 1.000000 |

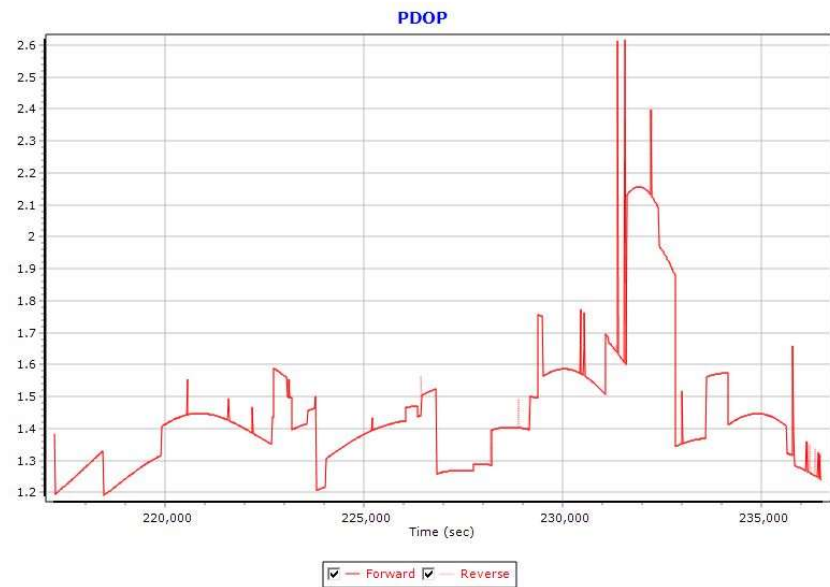
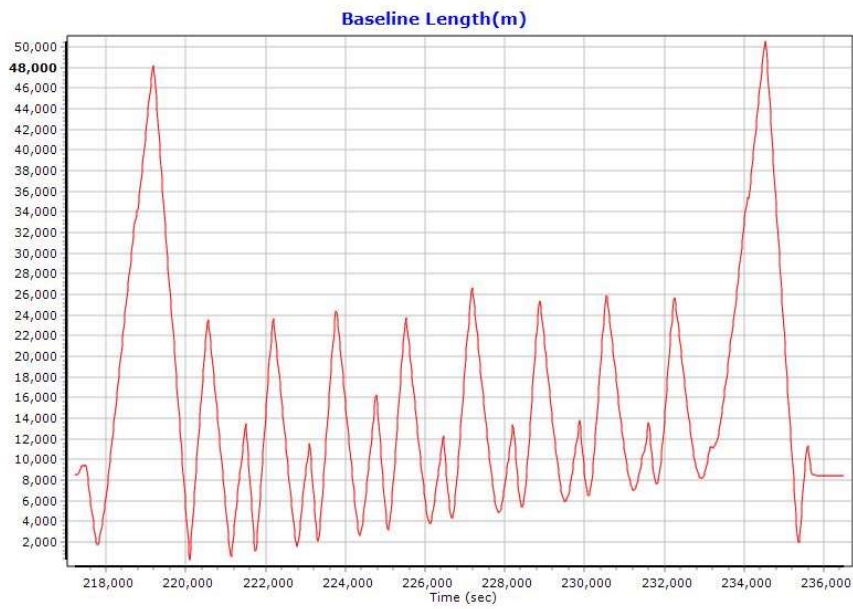
UTC Offset



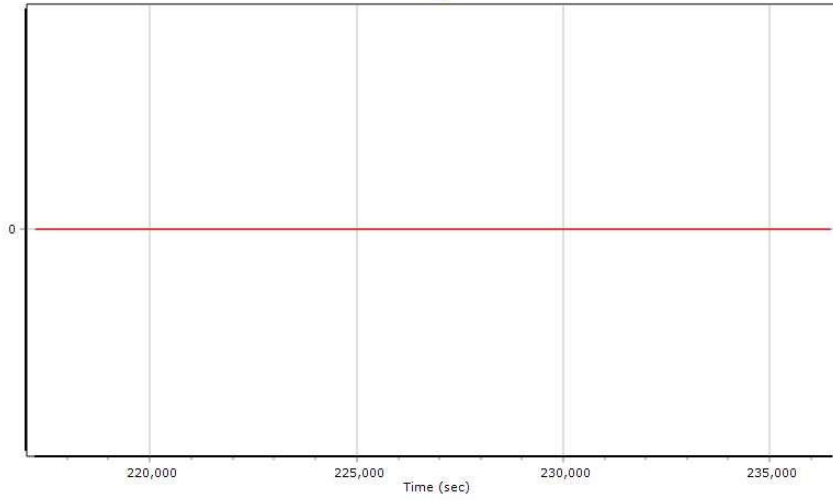






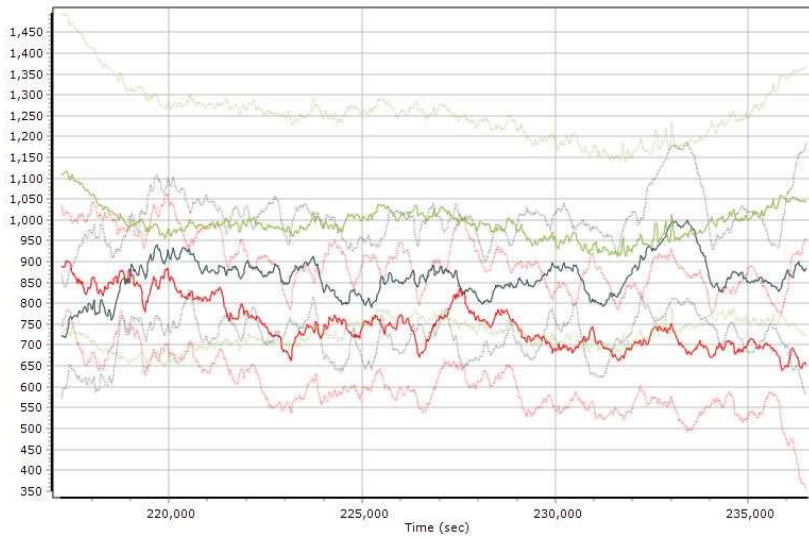


Processing Mode

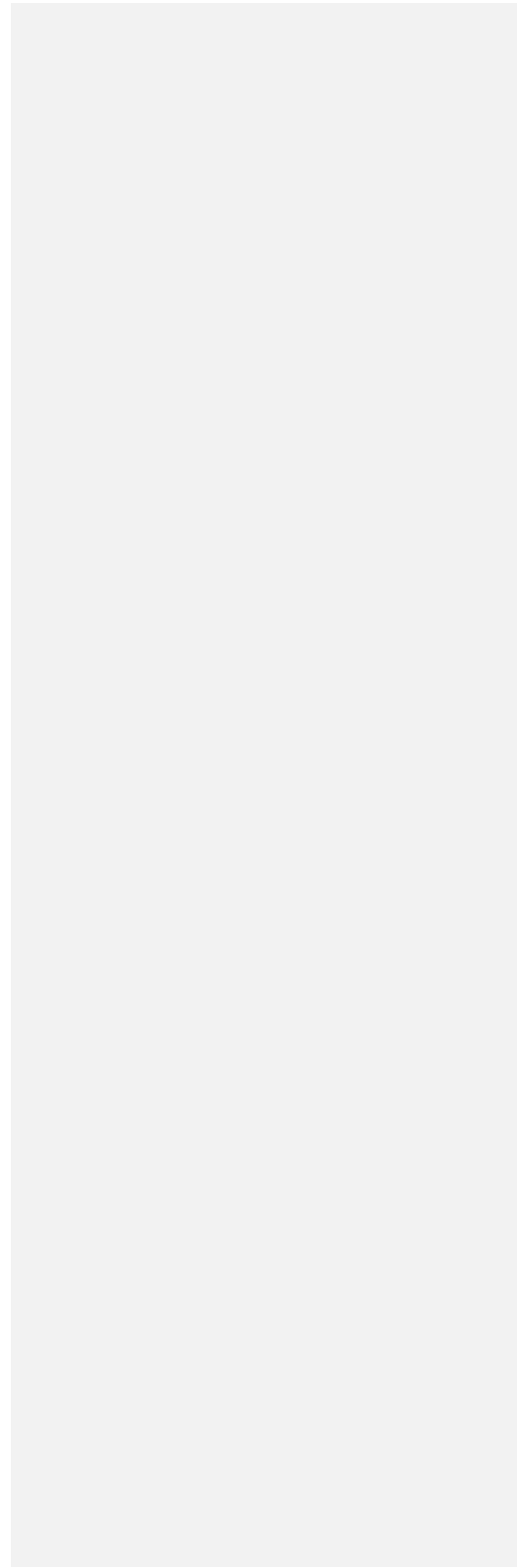
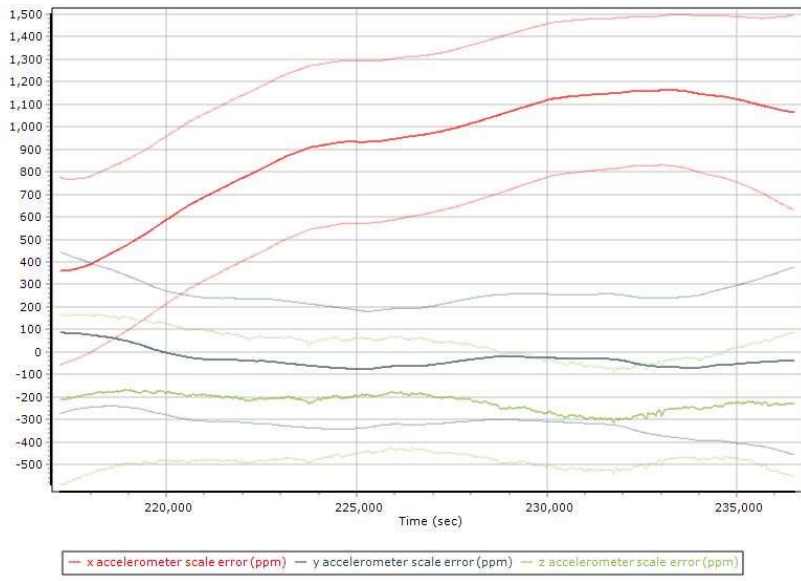


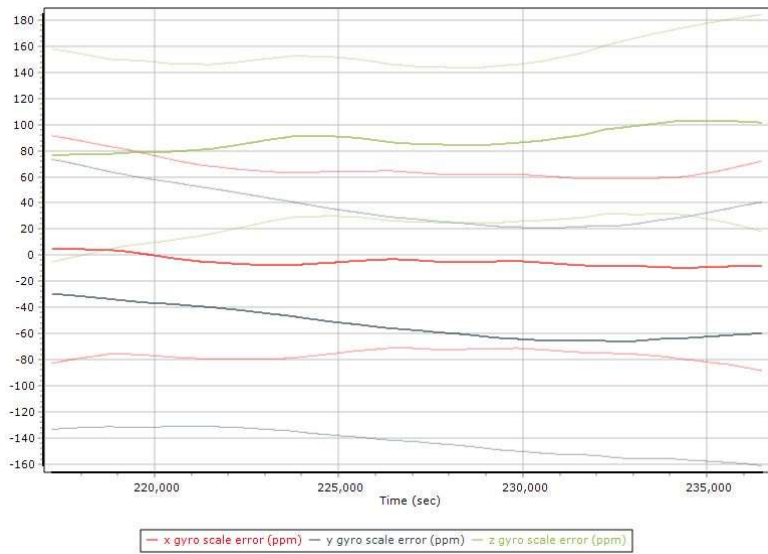
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

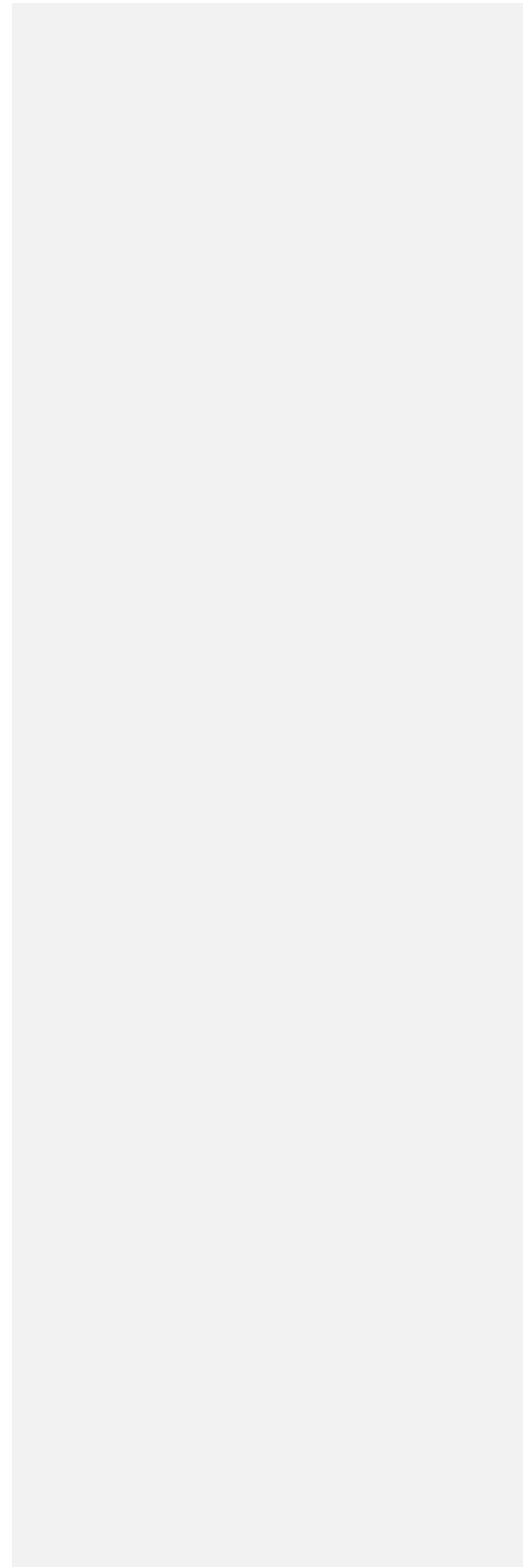
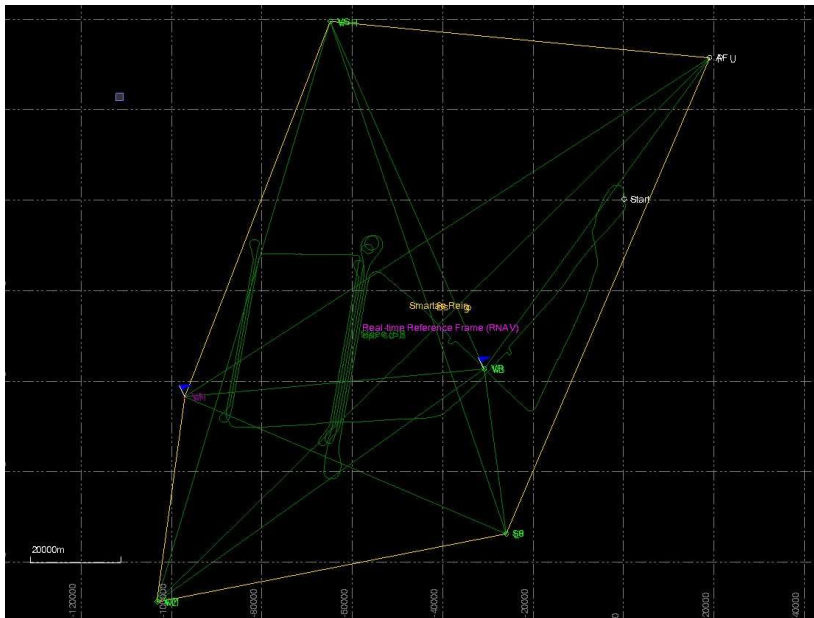


— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



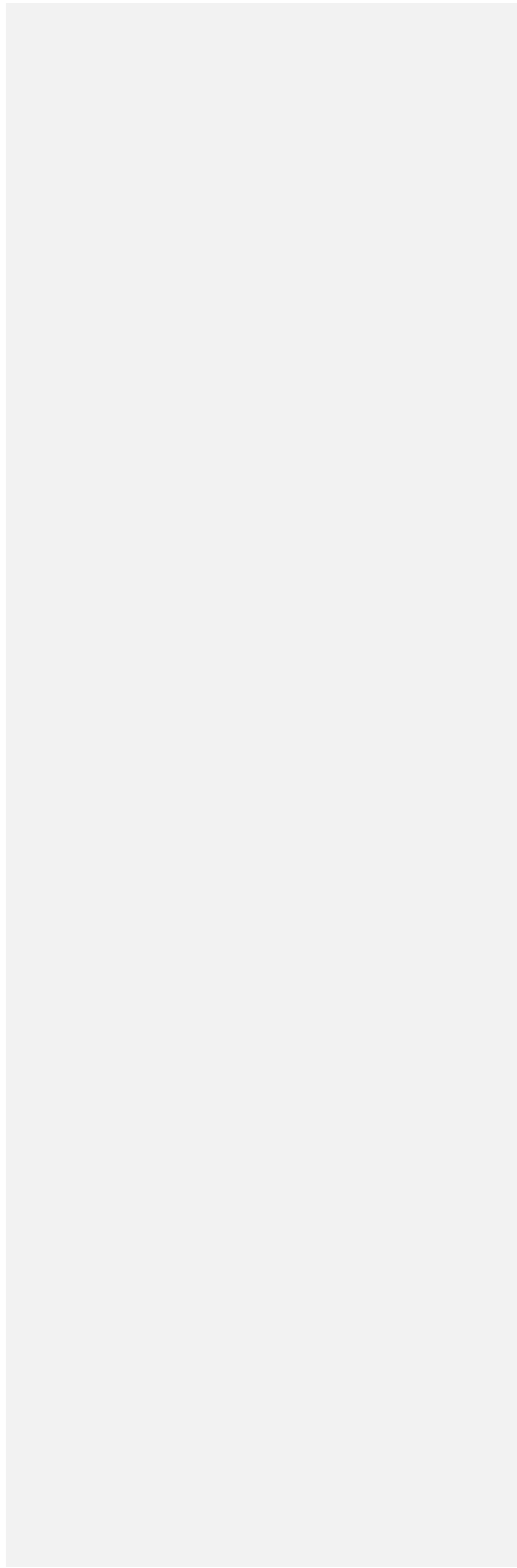


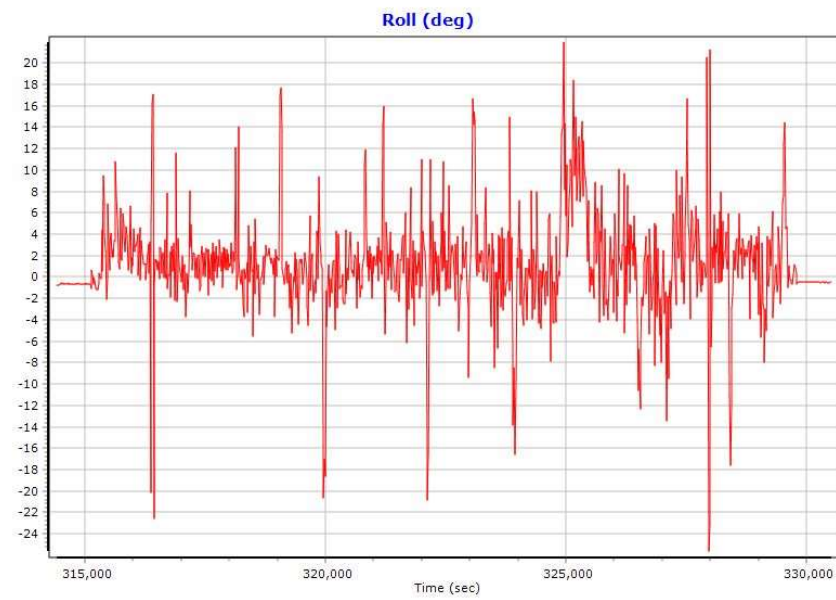
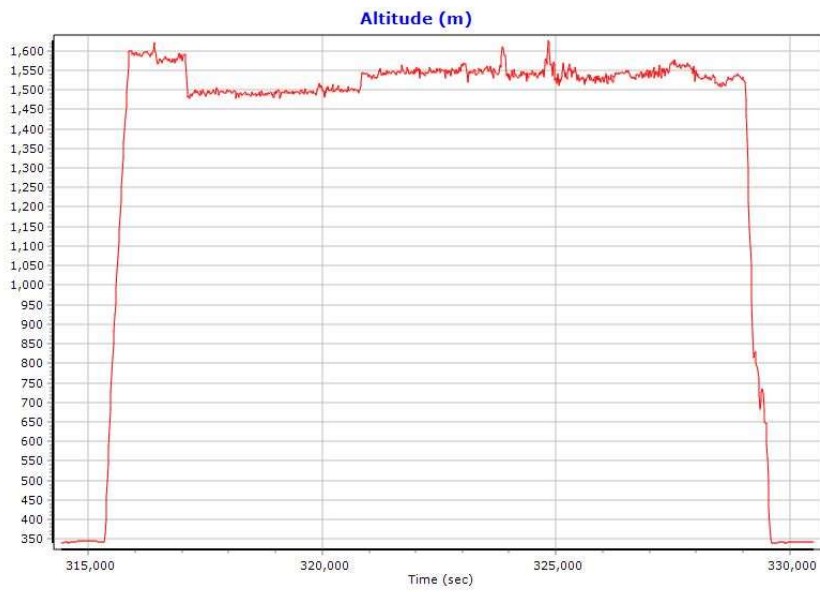
MNB190114A

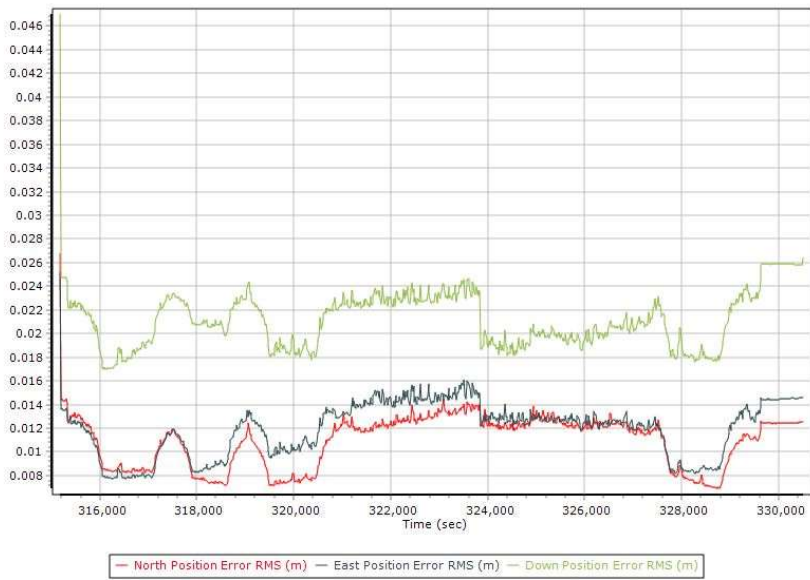
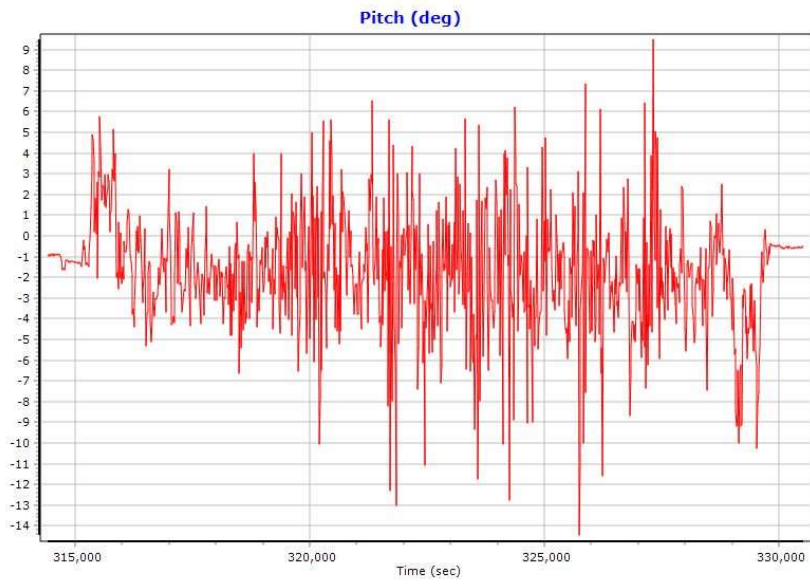


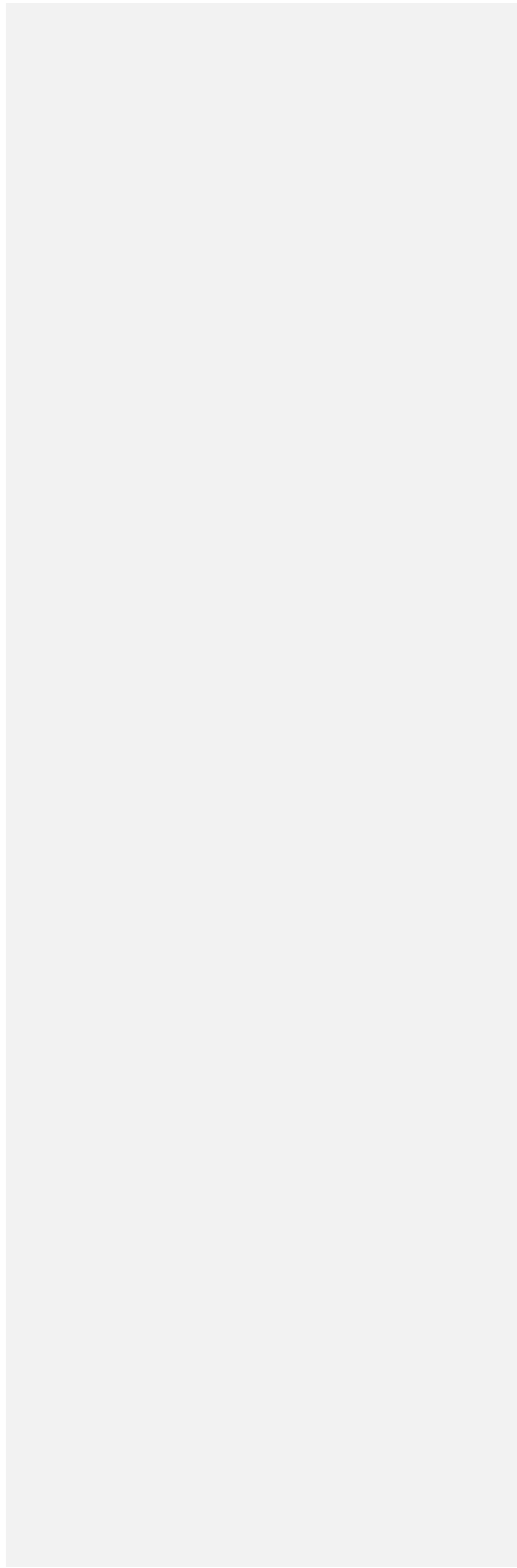
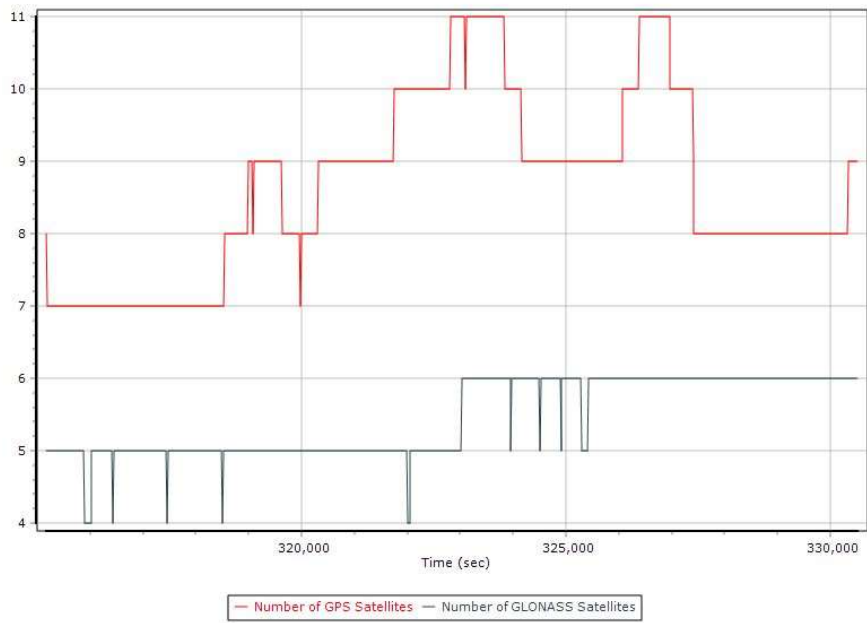
| | | | |
|-------------------------------------|---------------------------------------|---------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.150 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.061 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.992 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | <input type="range" value="10cm"/> | | |
| | <3cm 10cm 50cm 1m 10m | | |

| | | | |
|-------------------------------------|-----------------------------------------|---------------|-------------|
| Timing | | | |
| Start | <input type="text" value="314421.000"/> | Data | Incr. (sec) |
| End | <input type="text" value="330519.000"/> | Output Record | 0.005000 |
| <input checked="" type="checkbox"/> | Entire time interval | IMU | 0.005000 |
| <input checked="" type="checkbox"/> | Seconds of start week | Primary GNSS | 1.000000 |
| UTC Offset | <input type="text" value="18.000"/> | | |

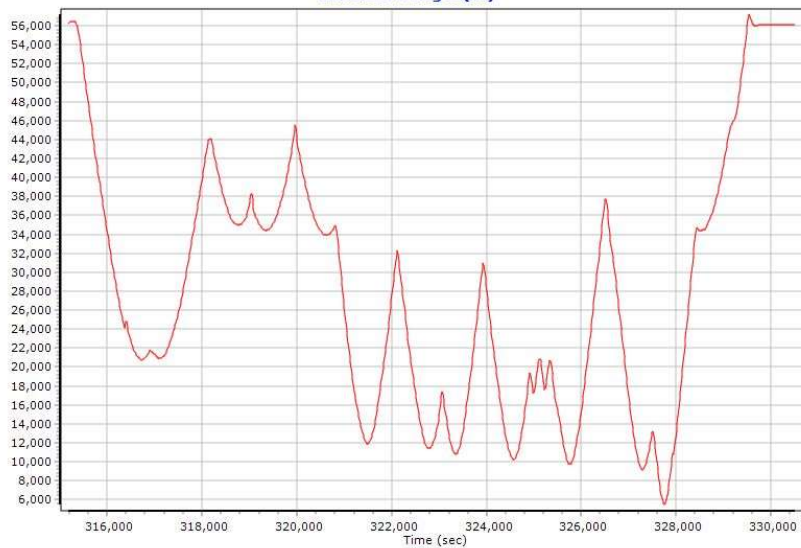




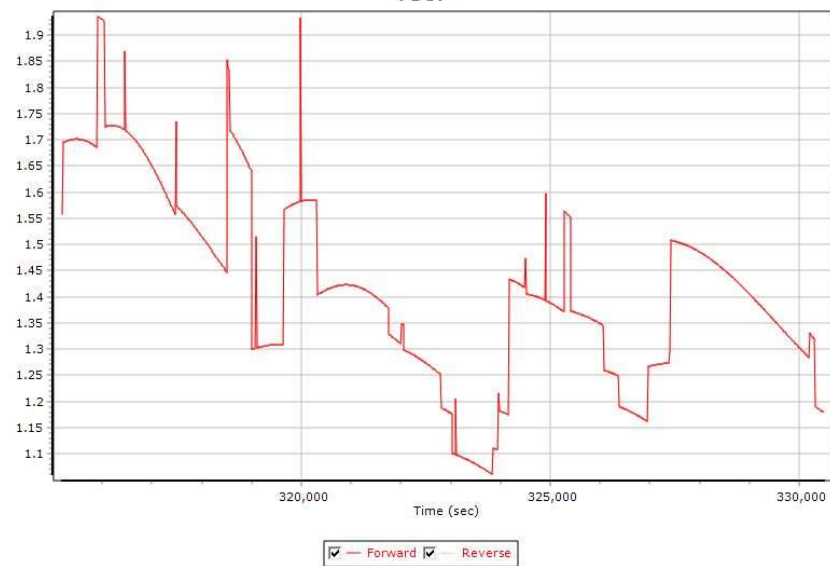




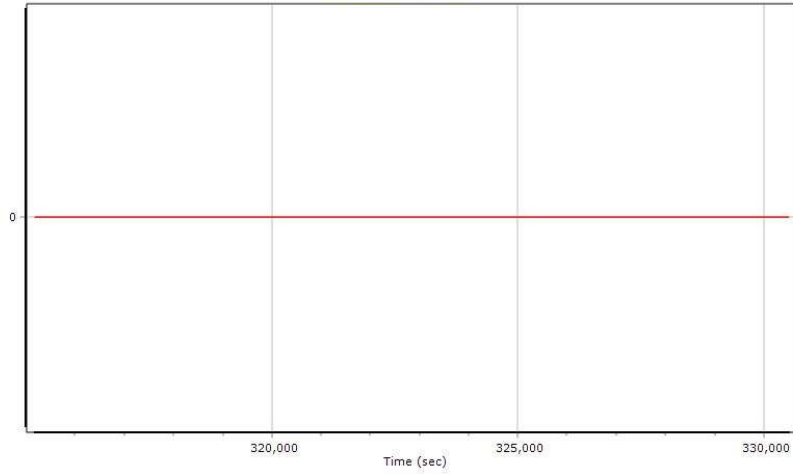
Baseline Length(m)



PDOP

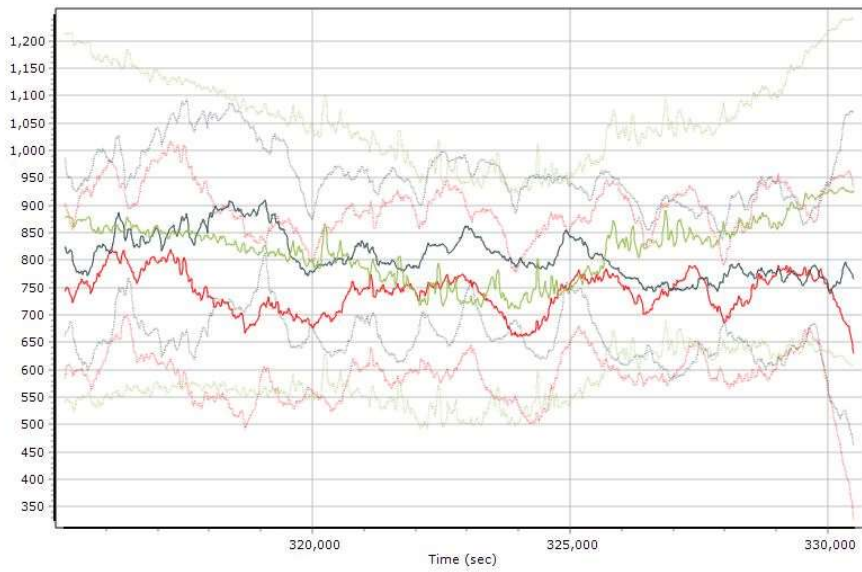


Processing Mode

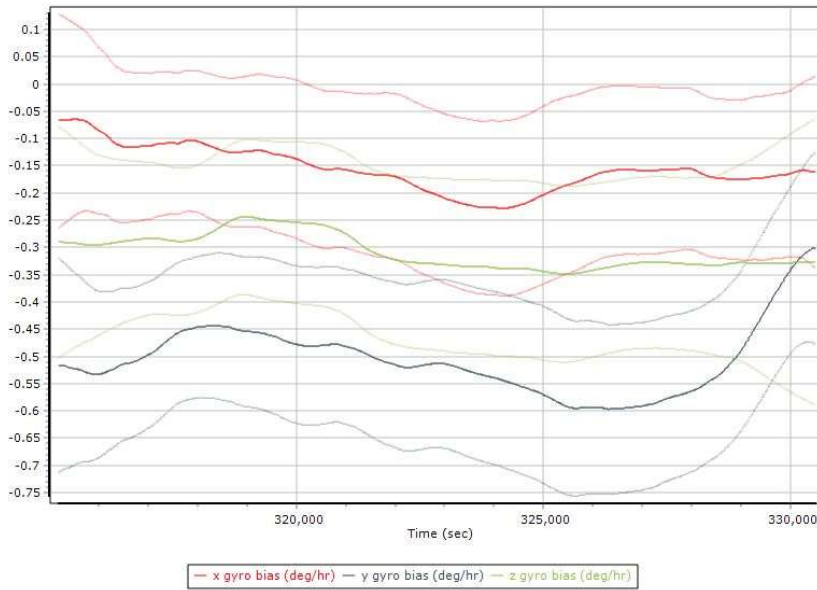
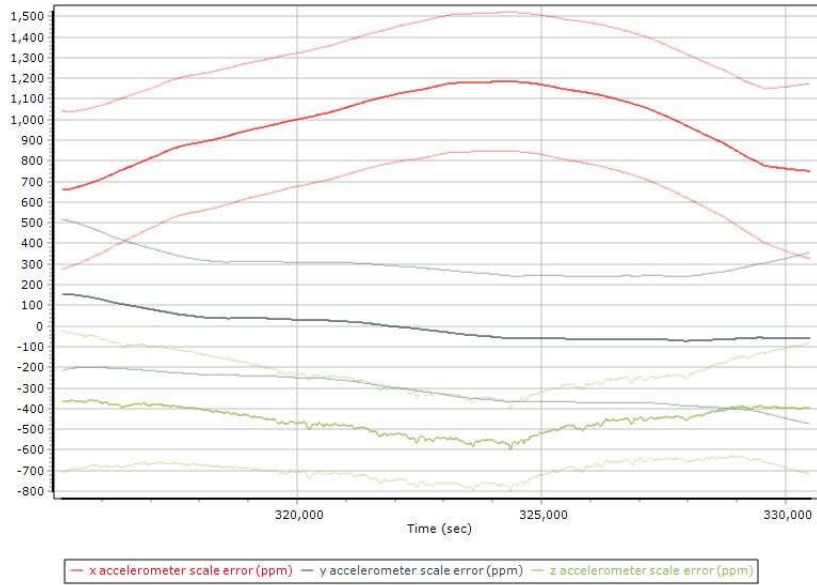


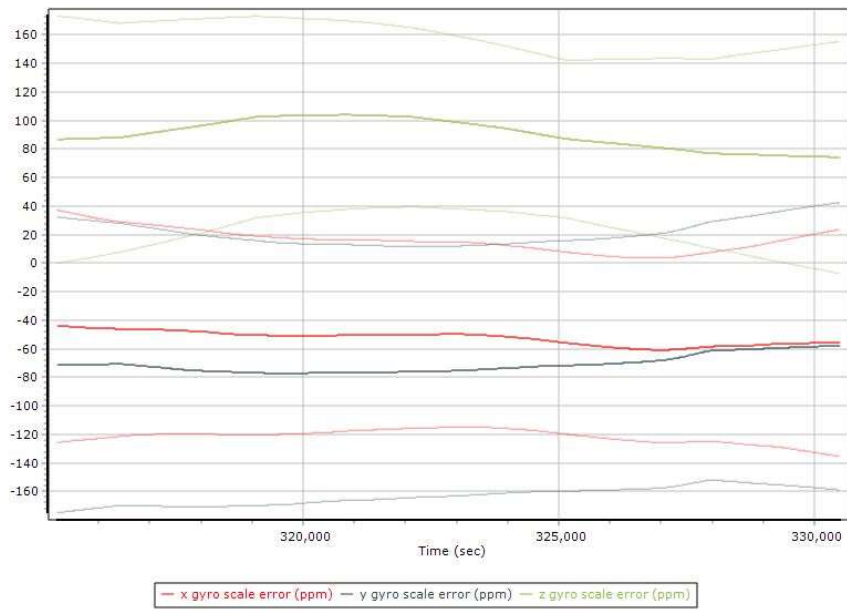
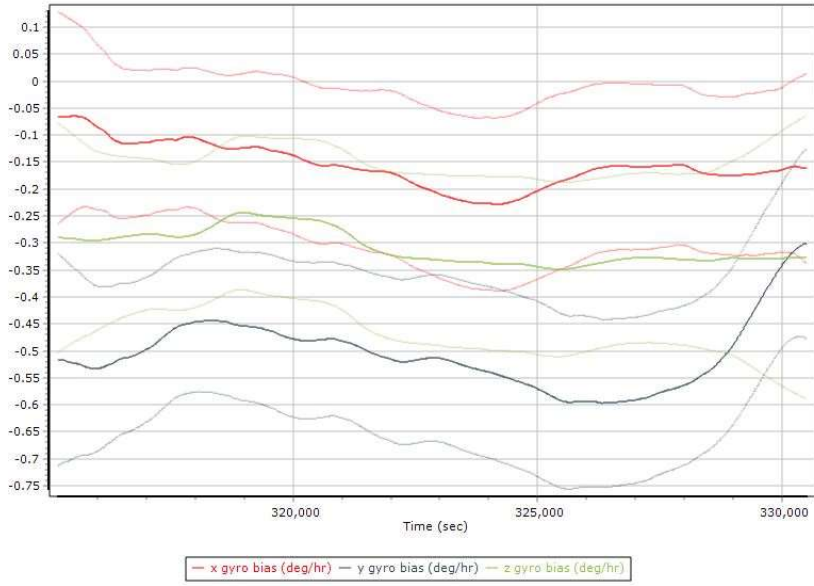
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

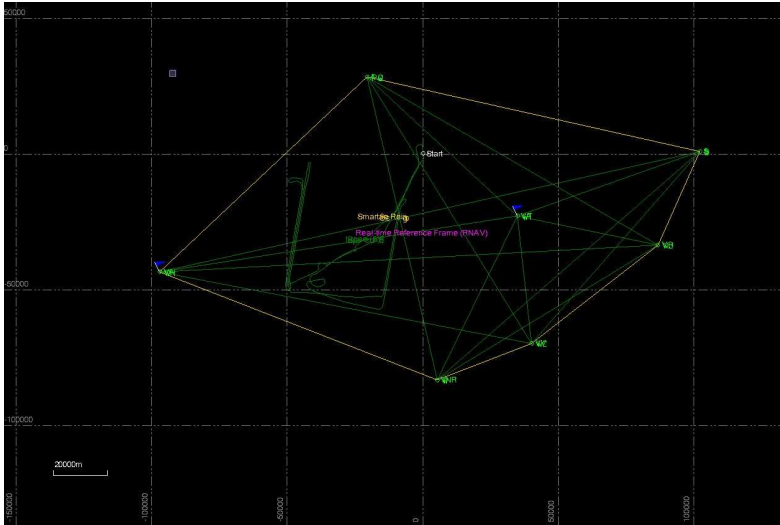


— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)





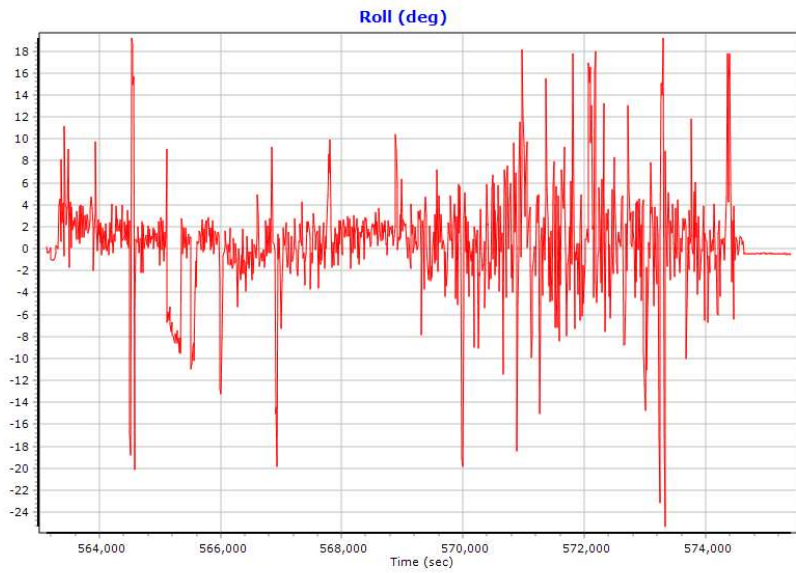
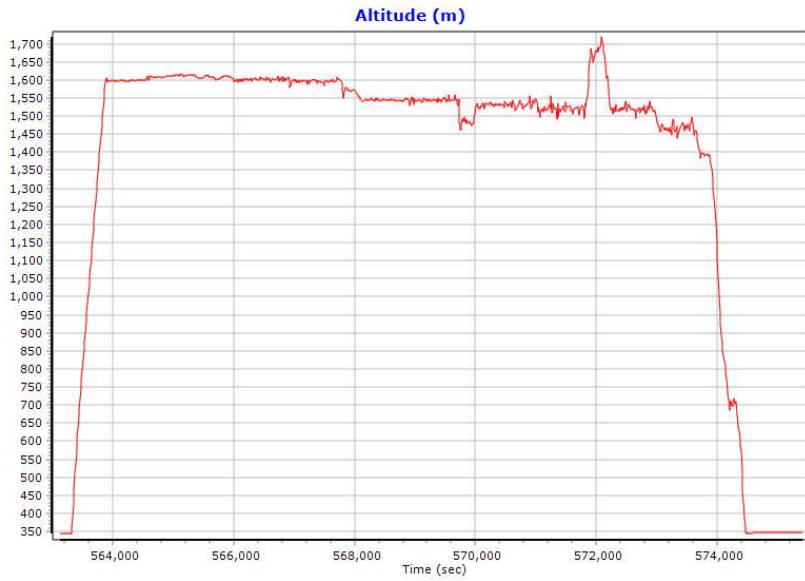
MNB19117A

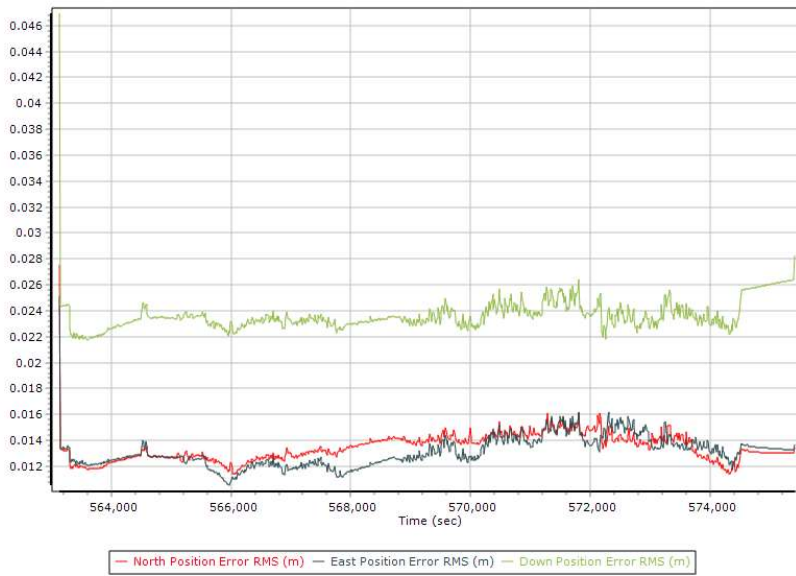
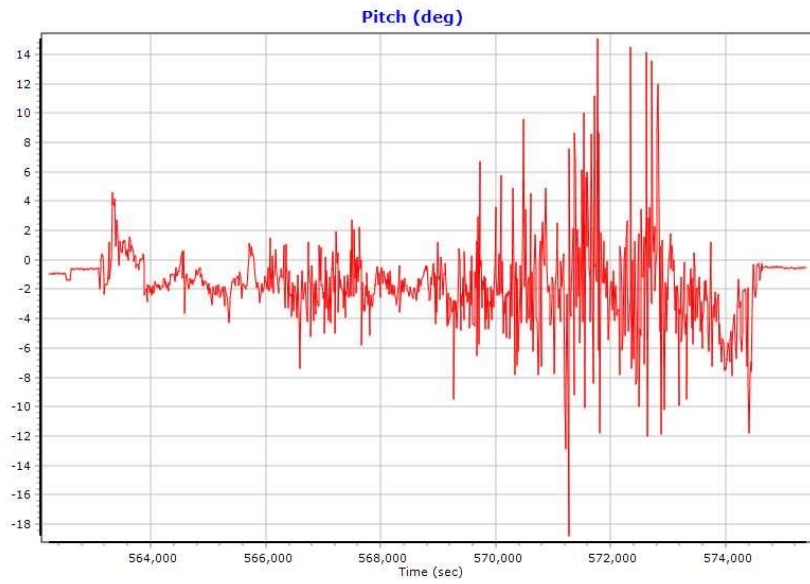


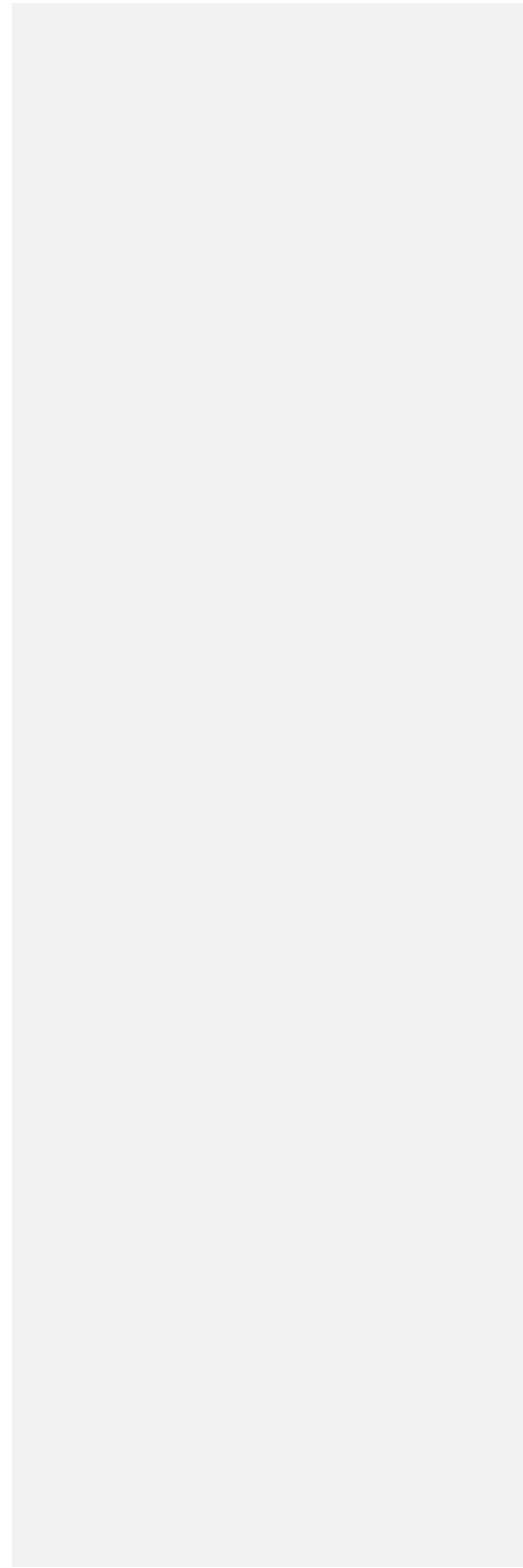
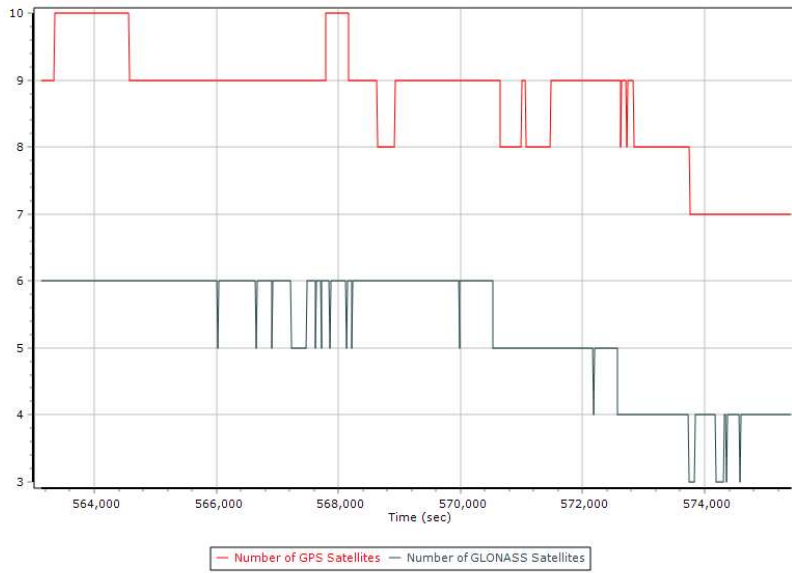
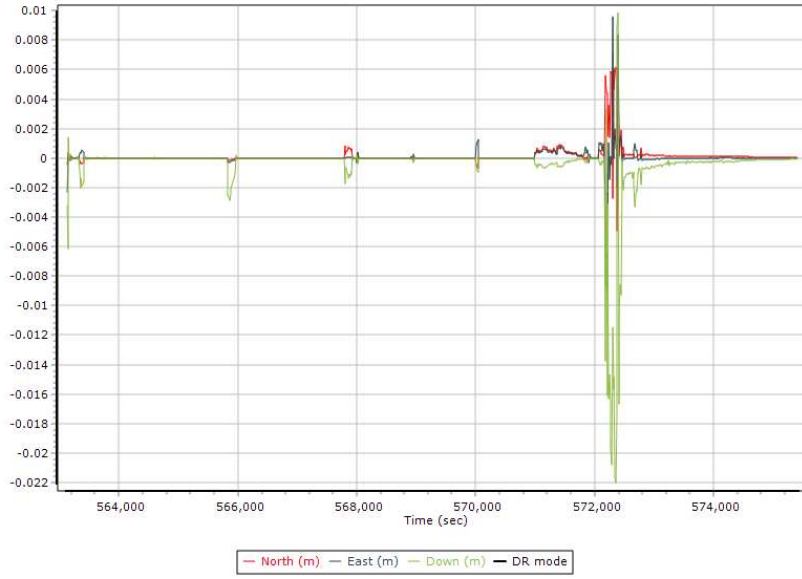
| | | | |
|---------------------------------------------------------------------------------------------------------------------------------------------------------------|---------------------------------------|---------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.150 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.061 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.992 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | | | |
| <input checked="" type="checkbox"/> <3cm <input type="checkbox"/> 10cm <input type="checkbox"/> 50cm <input type="checkbox"/> 1m <input type="checkbox"/> 10m | | | |

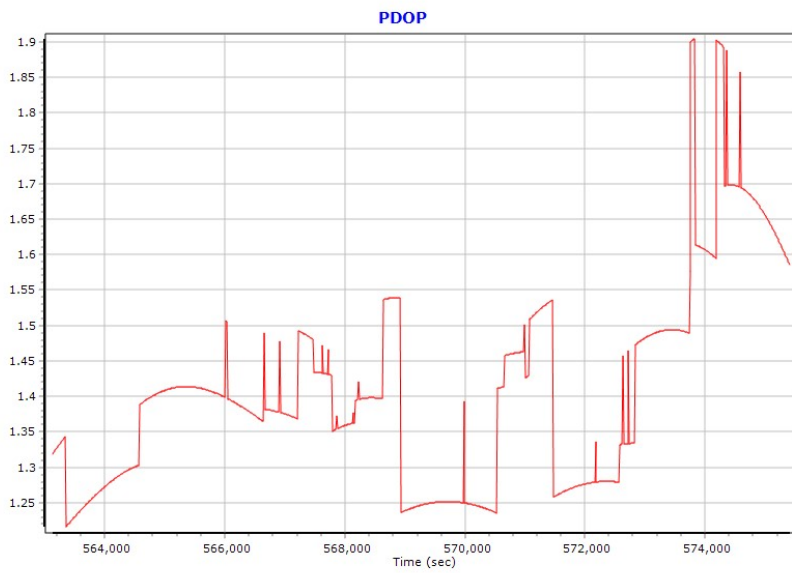
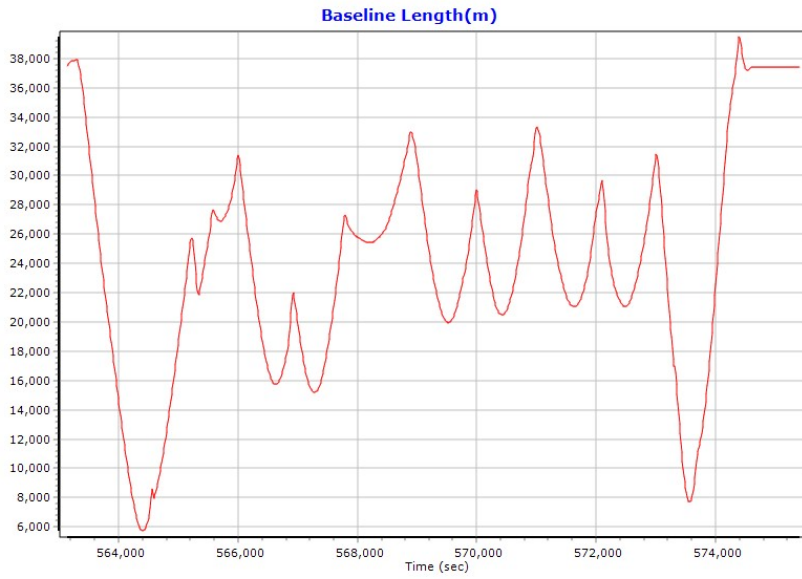
Project Settings

| <ul style="list-style-type: none"> General Information Units View Rover Import Satellite Selection GNSS-Inertial Processor Timing Algorithms Initialization | <p>Timing</p> <p>Start: <input type="text" value="562228.000"/></p> <p>End: <input type="text" value="575420.000"/></p> <p><input checked="" type="checkbox"/> Entire time interval</p> <p><input checked="" type="checkbox"/> Seconds of start week</p> <p>UTC Offset: <input type="text" value="18.000"/></p> <table border="1"> <thead> <tr> <th>Data</th> <th>Incr. (sec)</th> </tr> </thead> <tbody> <tr> <td>Output Record</td> <td><input type="text" value="0.005000"/></td> </tr> <tr> <td>IMU</td> <td><input type="text" value="0.005000"/></td> </tr> <tr> <td>Primary GNSS</td> <td><input type="text" value="1.000000"/></td> </tr> </tbody> </table> | Data | Incr. (sec) | Output Record | <input type="text" value="0.005000"/> | IMU | <input type="text" value="0.005000"/> | Primary GNSS | <input type="text" value="1.000000"/> |
|-----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|------|-------------|---------------|---------------------------------------|-----|---------------------------------------|--------------|---------------------------------------|
| Data | Incr. (sec) | | | | | | | | |
| Output Record | <input type="text" value="0.005000"/> | | | | | | | | |
| IMU | <input type="text" value="0.005000"/> | | | | | | | | |
| Primary GNSS | <input type="text" value="1.000000"/> | | | | | | | | |

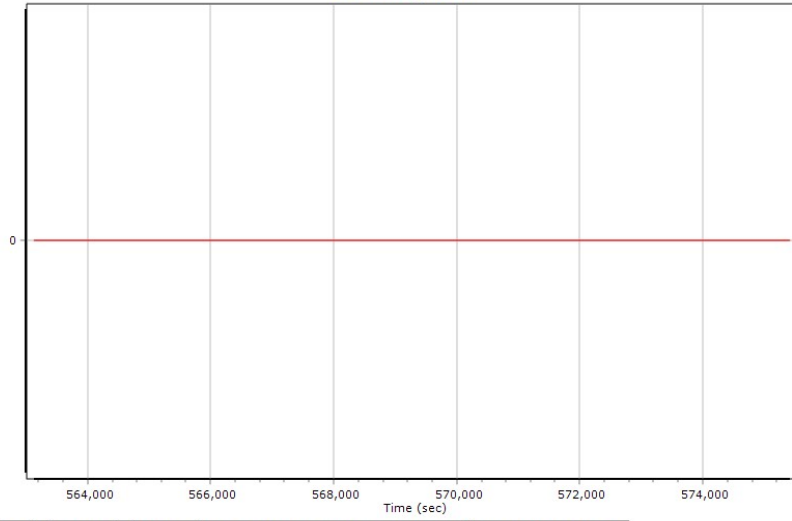




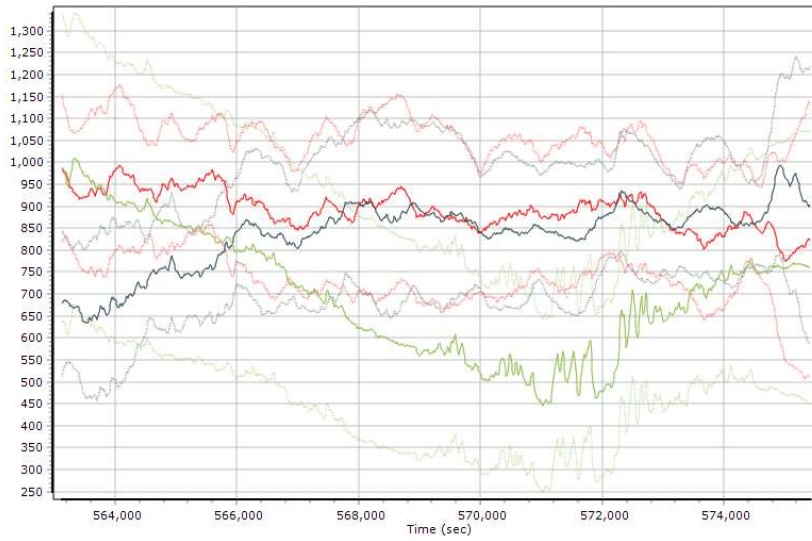




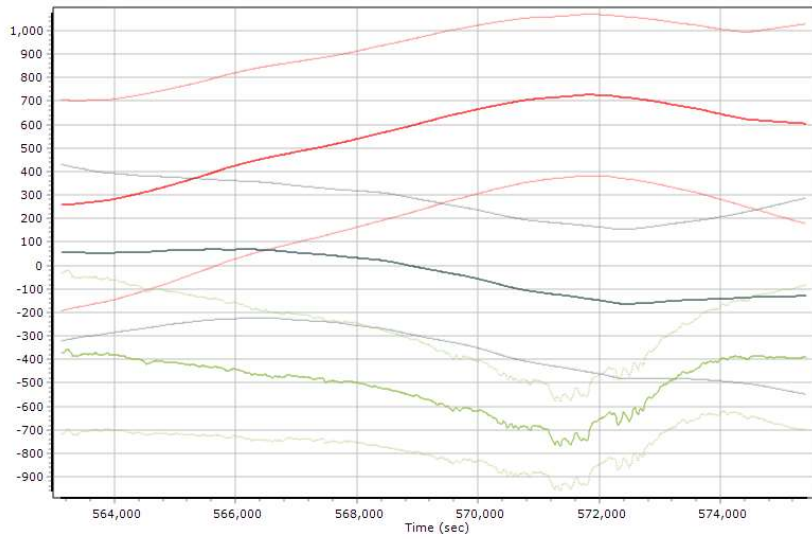
Processing Mode



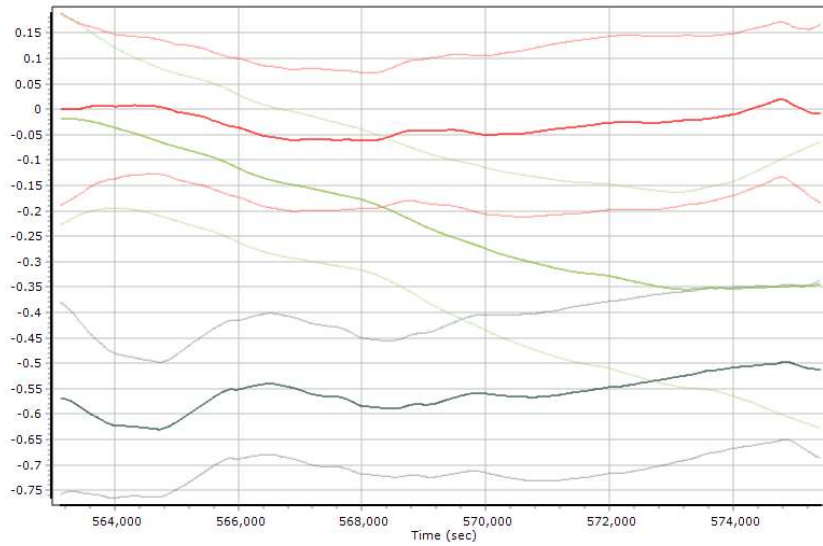
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



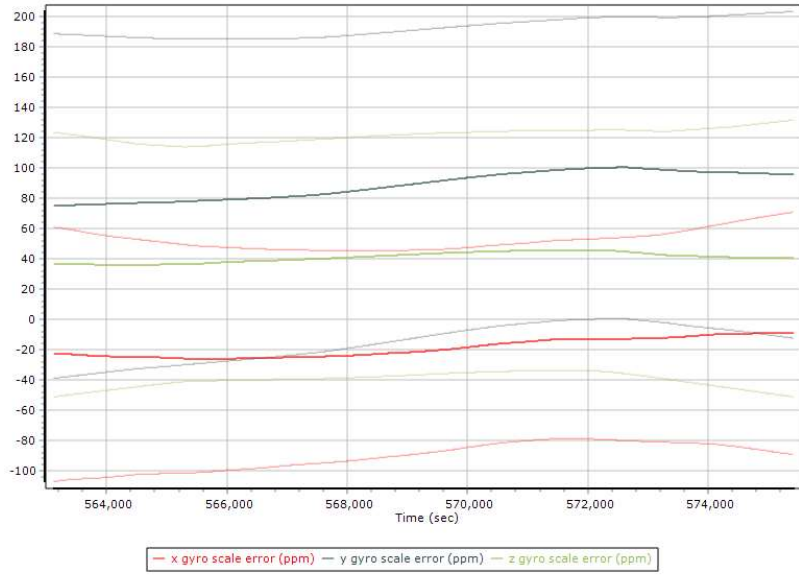
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



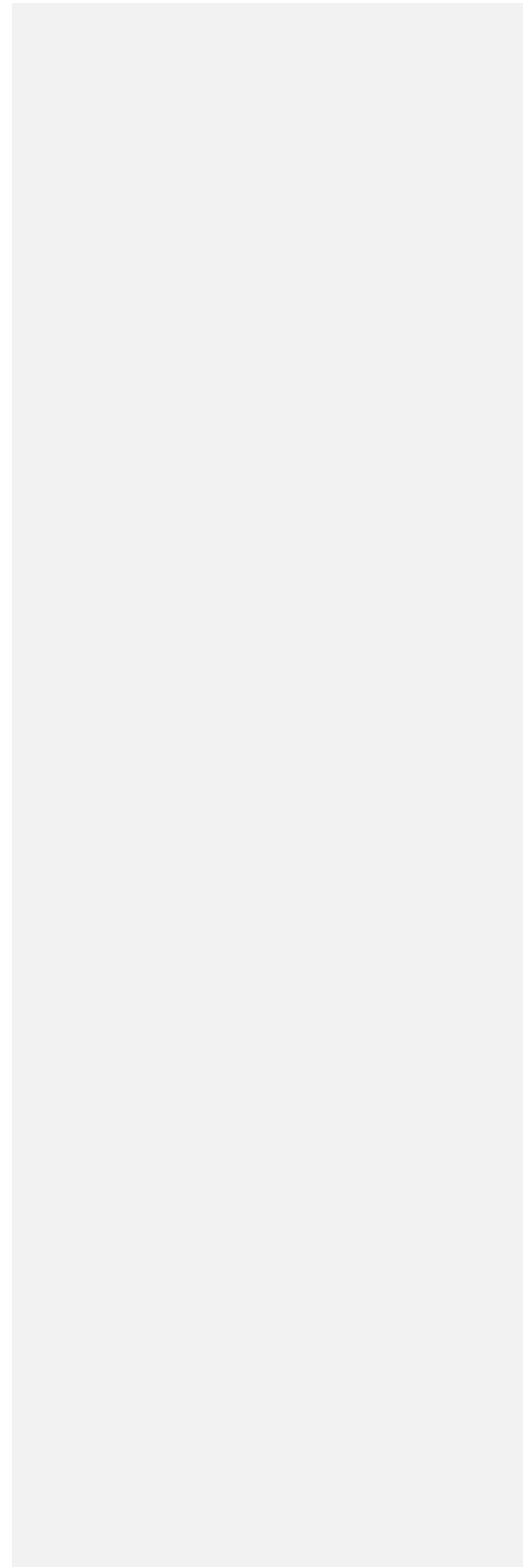
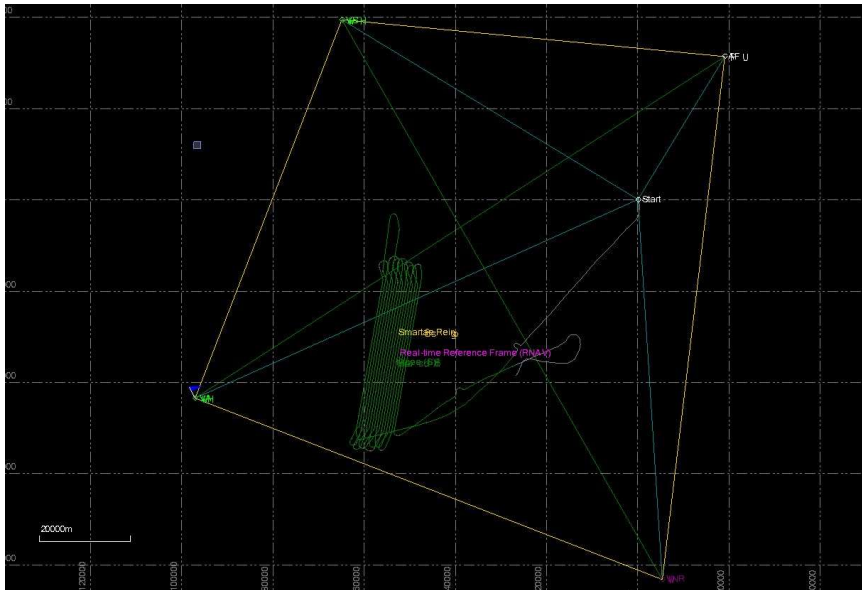
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)




MNB19119A



| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
|----------------------------|----------|----------------------------------|-----------|
| X | 0.034 m | X | 0.000 deg |
| Y | 0.018 m | Y | 0.000 deg |
| Z | -0.155 m | Z | 0.000 deg |

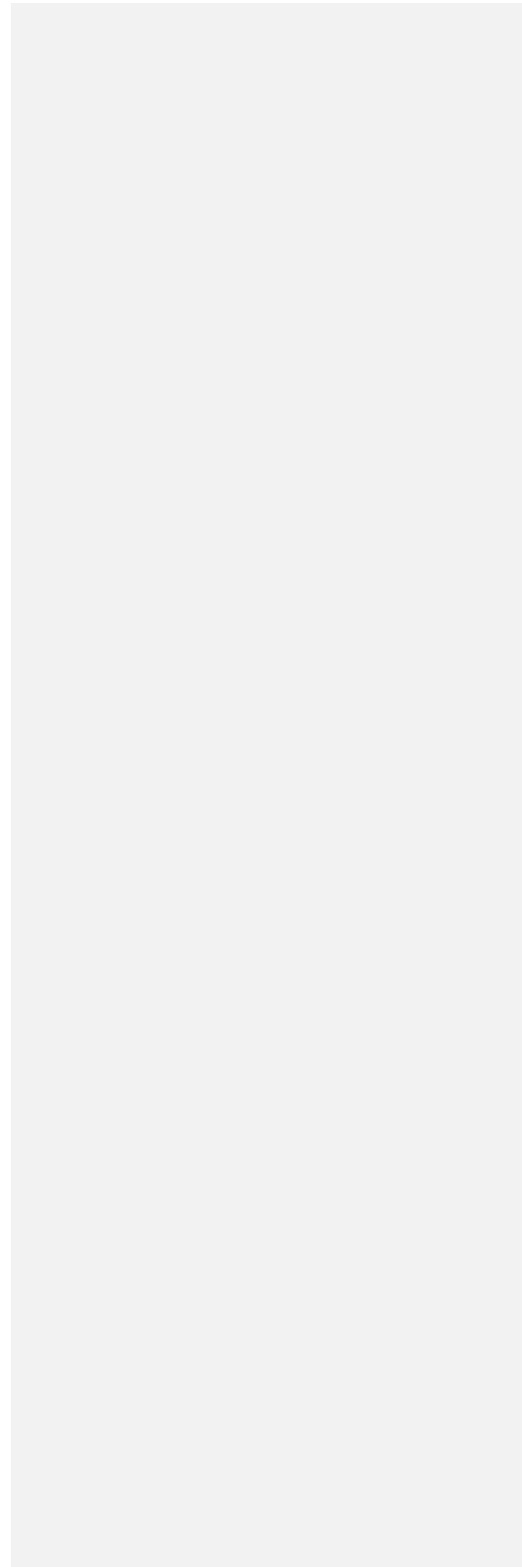
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
|-------------------------------------|----------|---------------------------------------|-----------|
| X | -0.150 m | X | 0.000 deg |
| Y | -0.061 m | Y | 0.000 deg |
| Z | -0.099 m | Z | 0.000 deg |

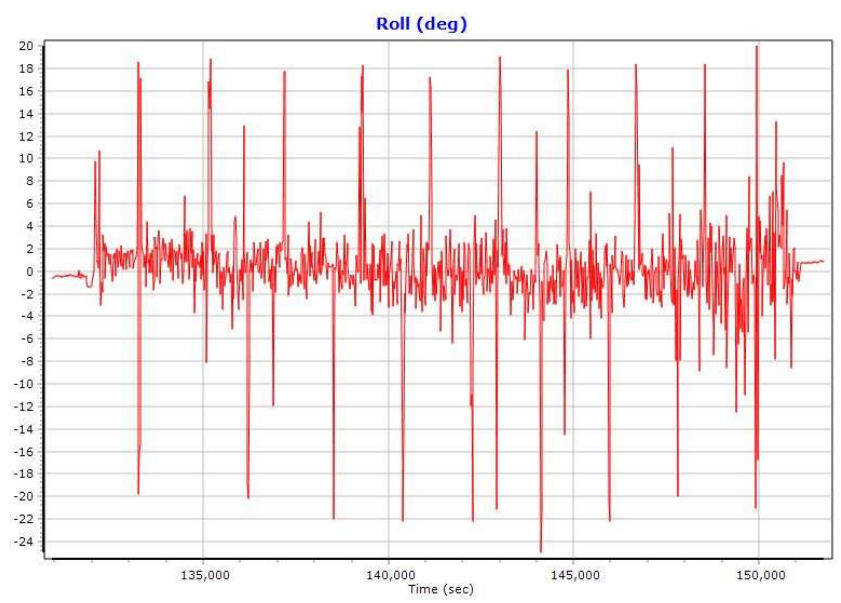
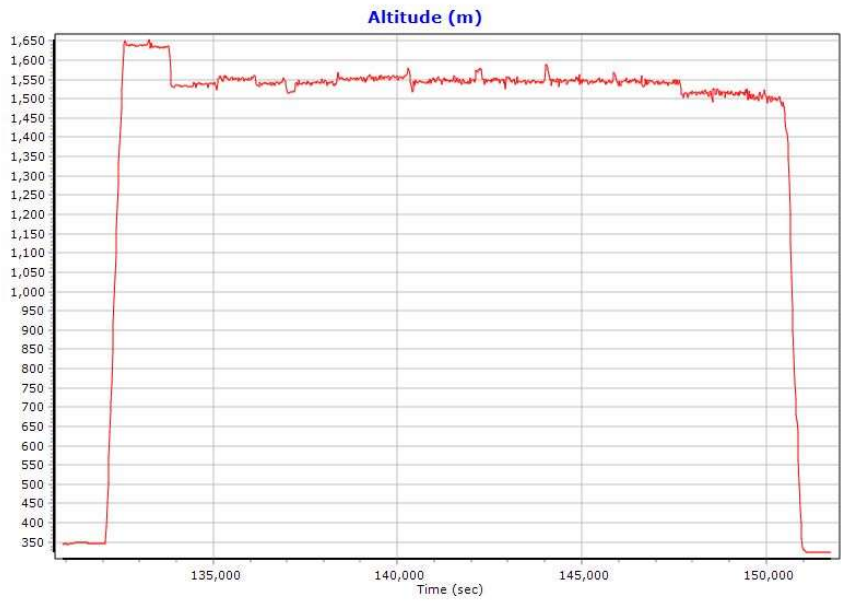
Standard Deviation 
 <3cm 10cm 50cm 1m 10m

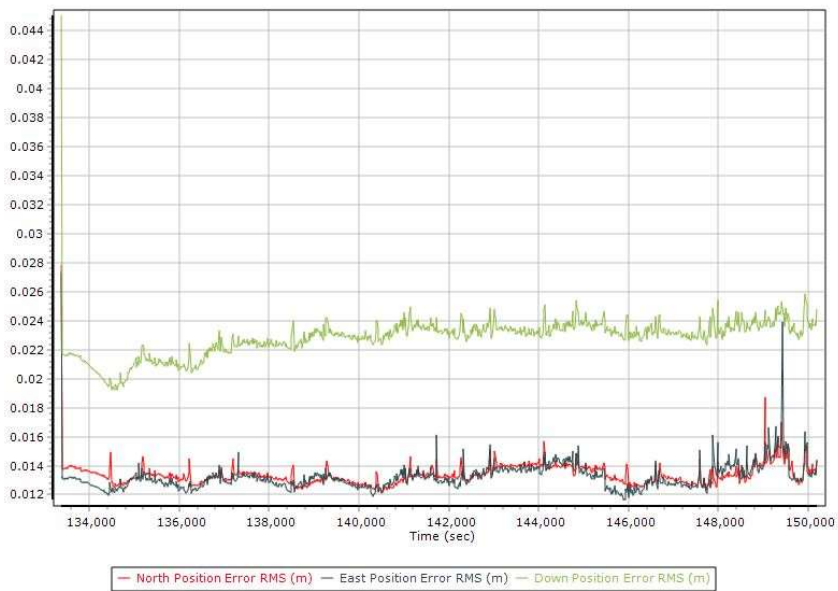
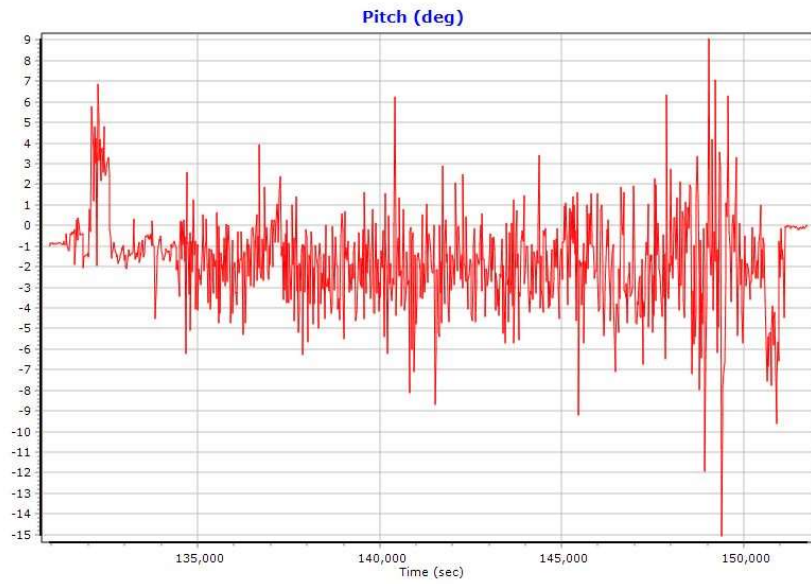
Timing

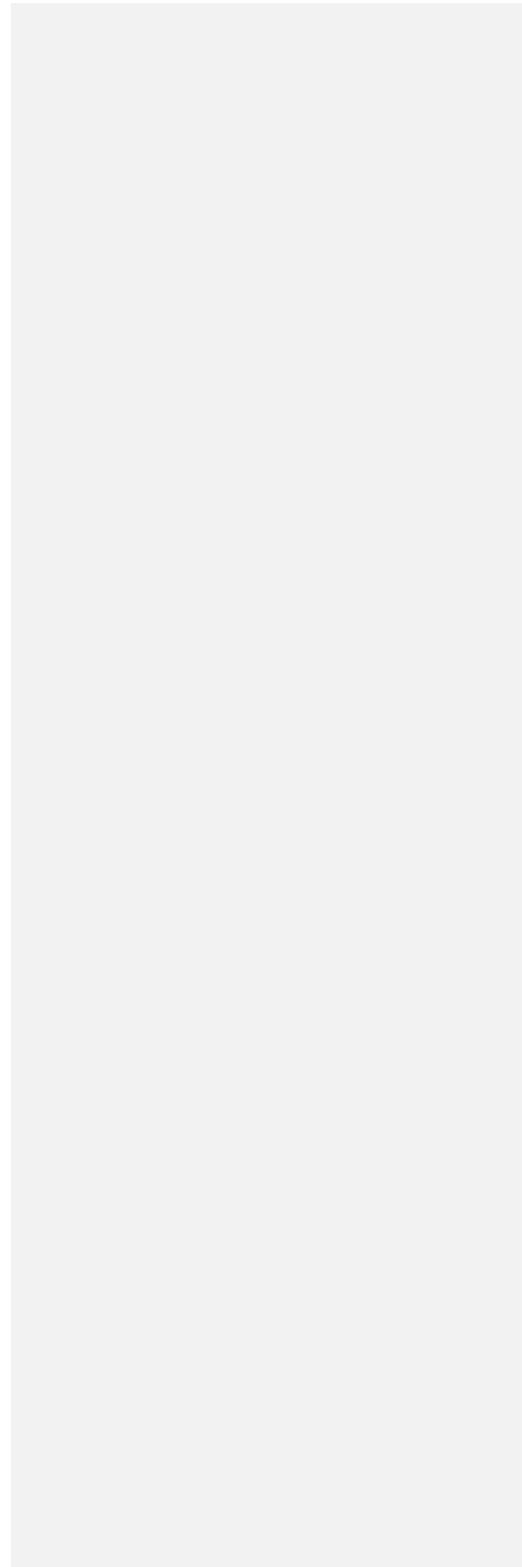
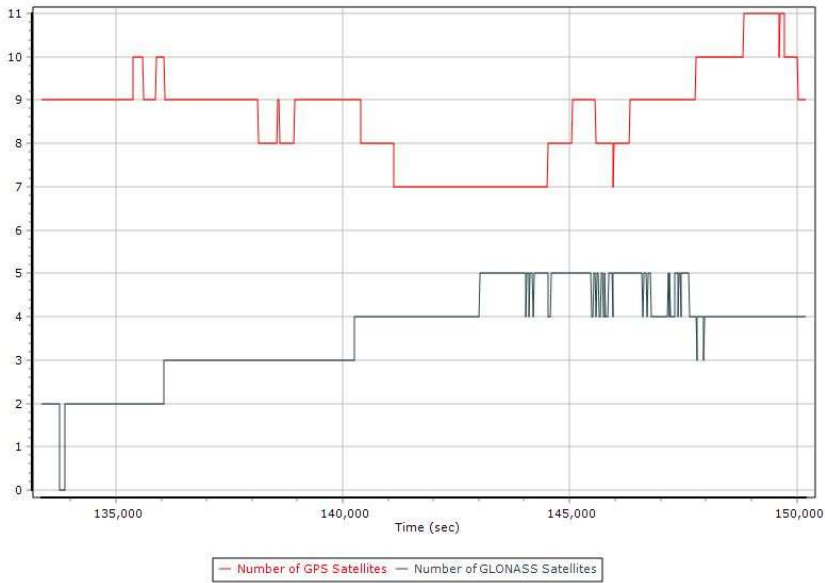
| | | | |
|-----------------------------------------------------------|------------|---------------|-------------|
| Start | 133366.113 | Data | Incr. (sec) |
| End | 150206.754 | Output Record | 0.005000 |
| <input type="checkbox"/> Entire time interval | | IMU | 0.005000 |
| <input checked="" type="checkbox"/> Seconds of start week | | Primary GNSS | 1.000000 |

UTC Offset 18.000

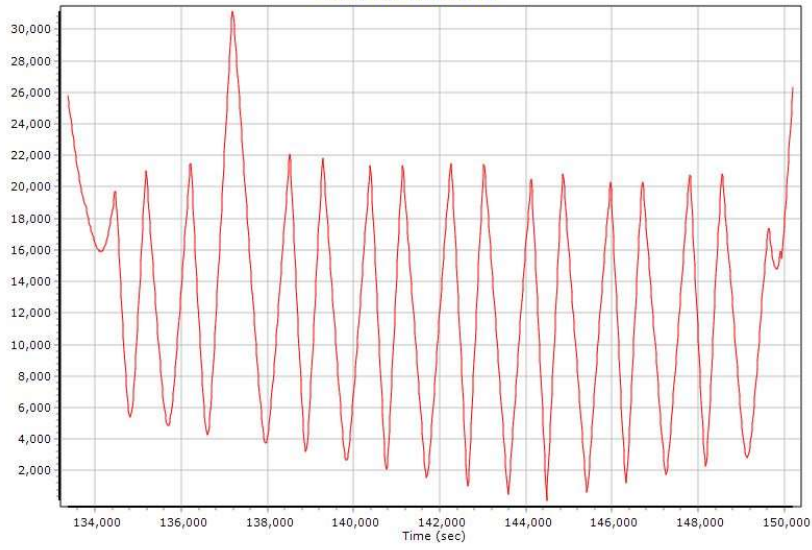




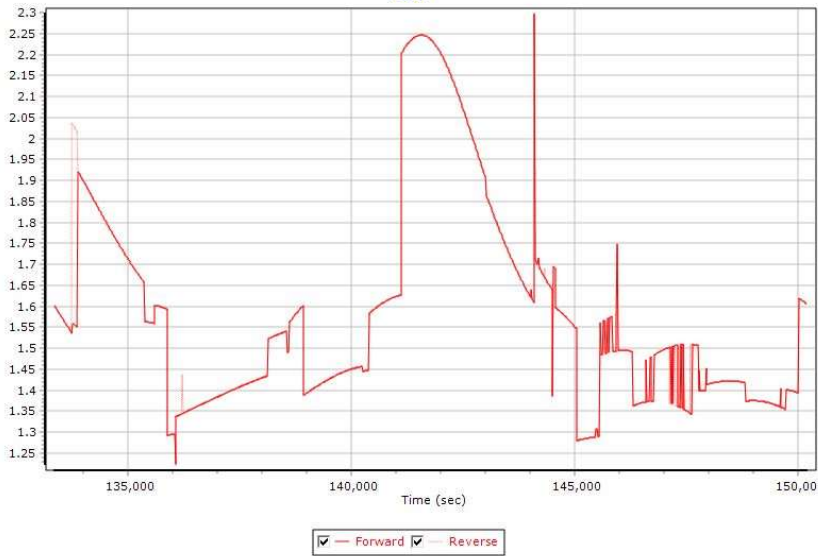




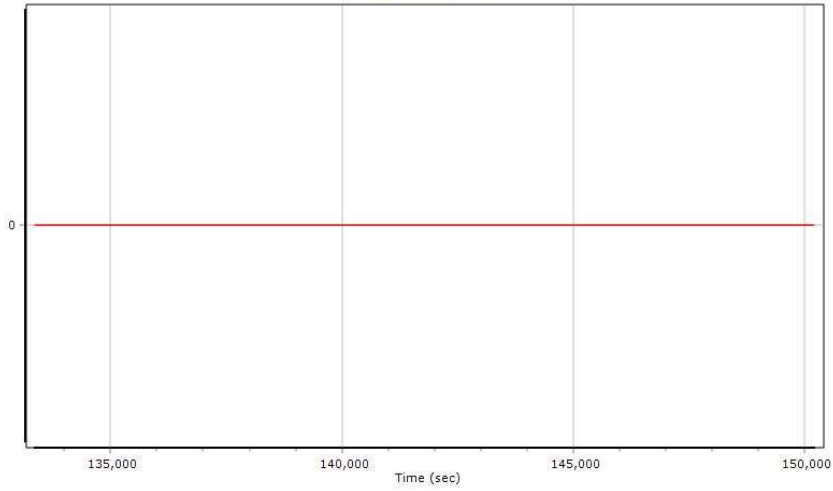
Baseline Length(m)



PDOP

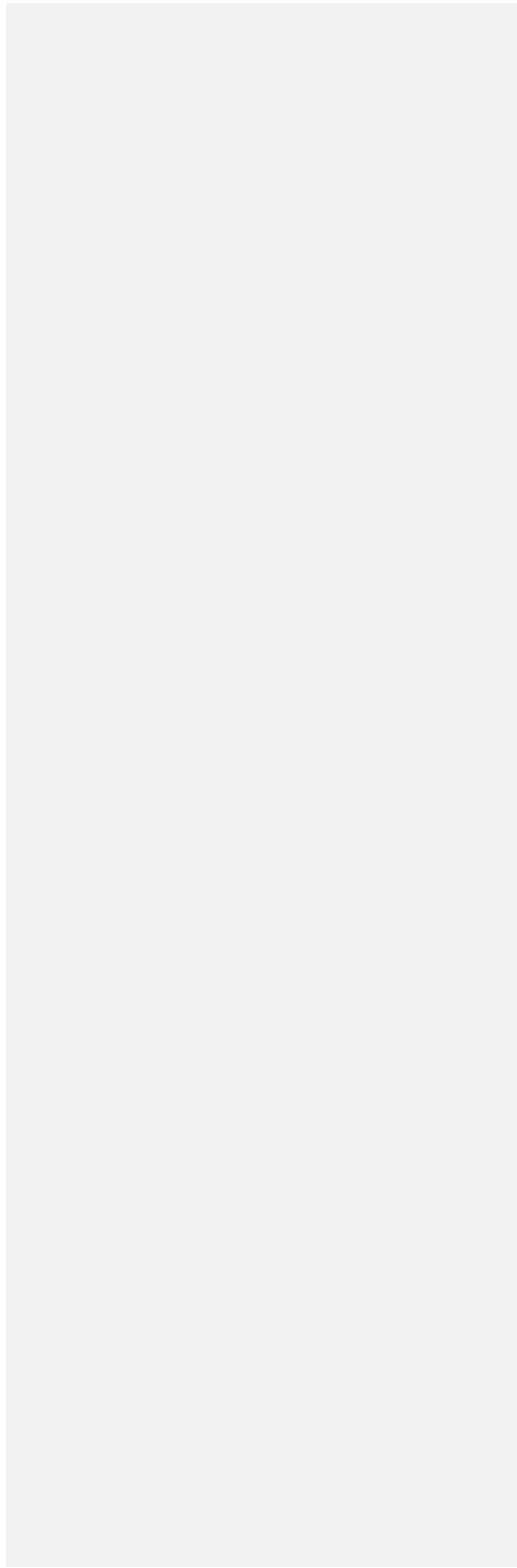


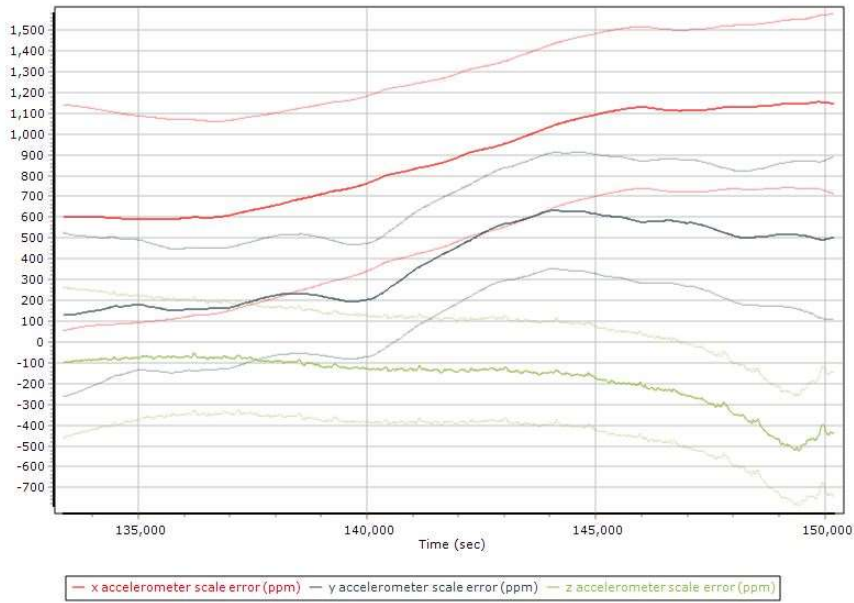
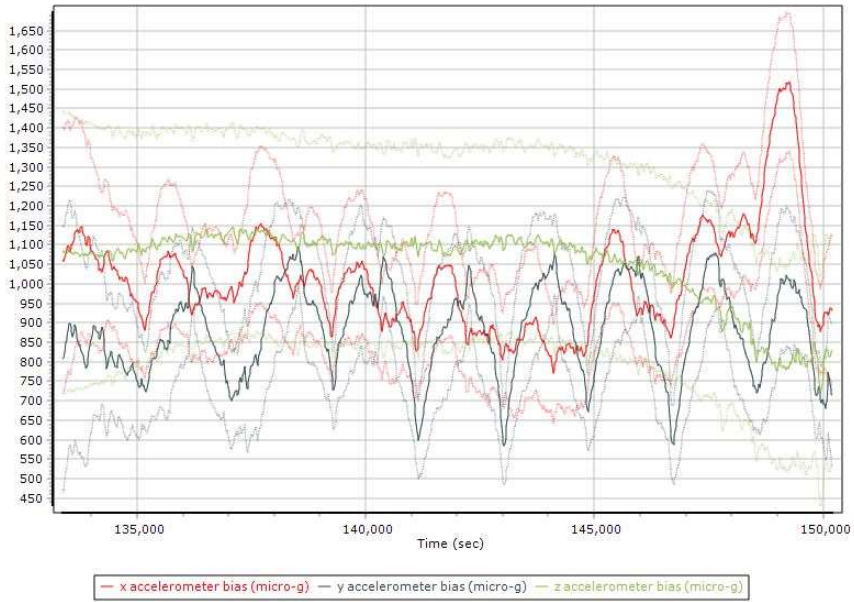
Processing Mode

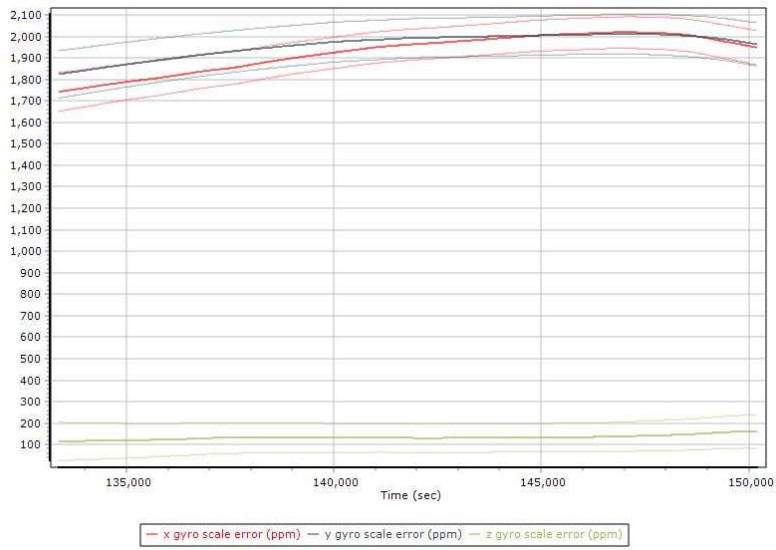


Forward Reverse

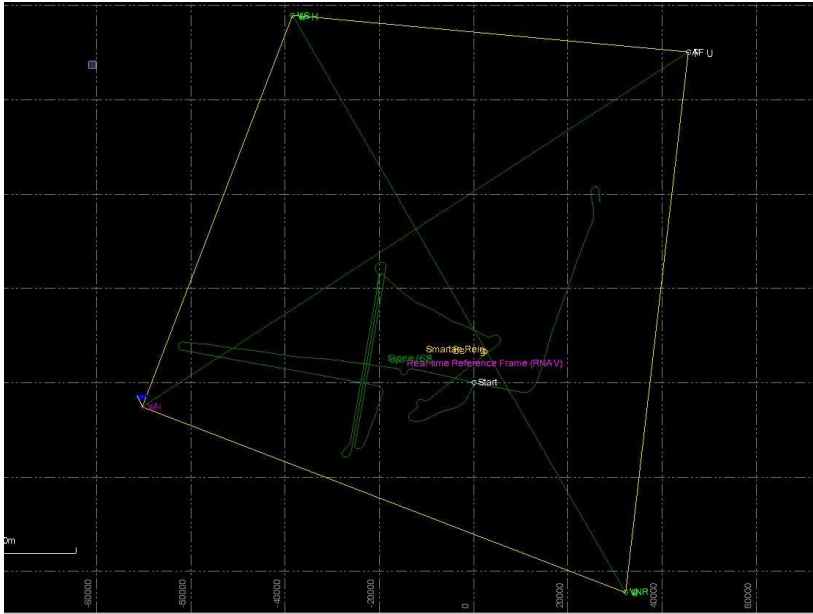
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



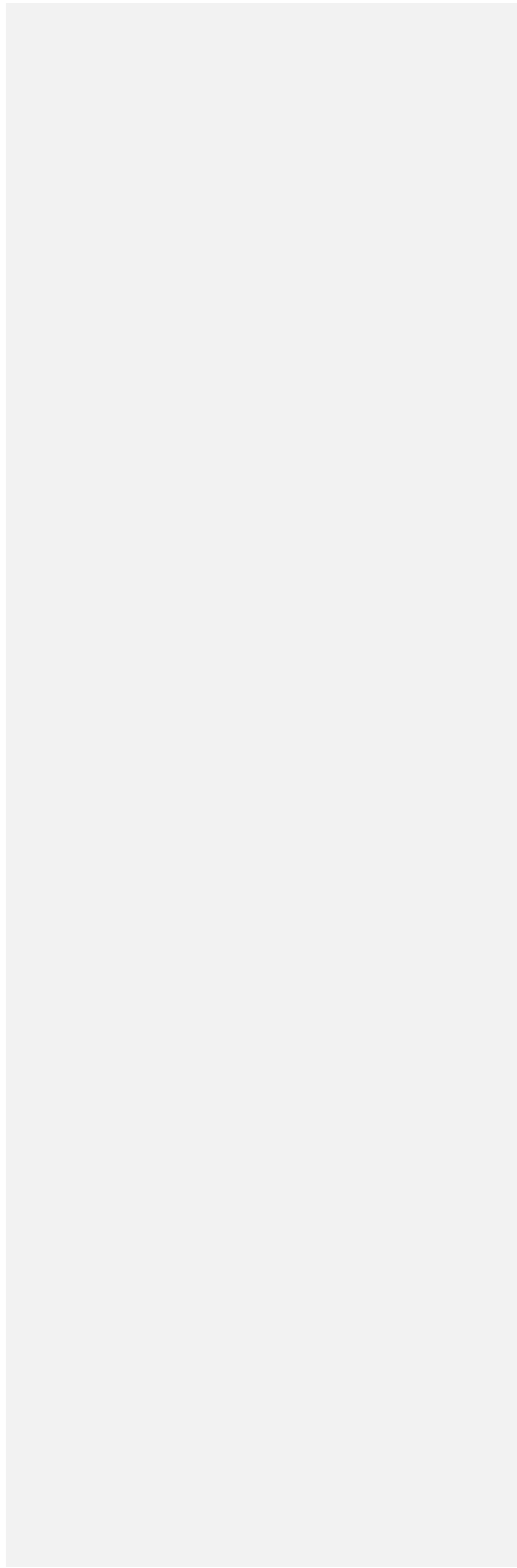




MNB19119B



| | | | |
|-------------------------------------|---------------------------------------|---------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.016 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.150 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.061 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.099 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | <input type="text" value="3cm"/> | | |
| | <3cm 10cm 50cm 1m 10m | | |



Timing

Start: 156063.000

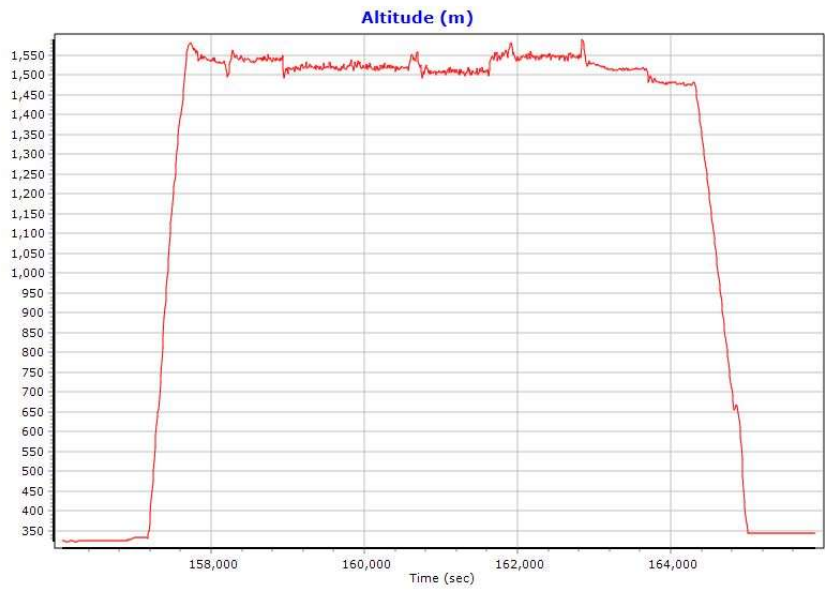
End: 165884.000

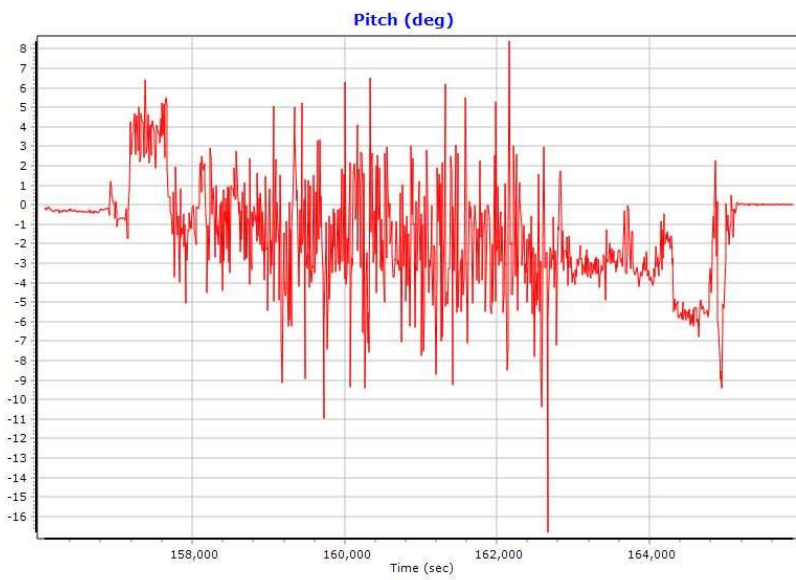
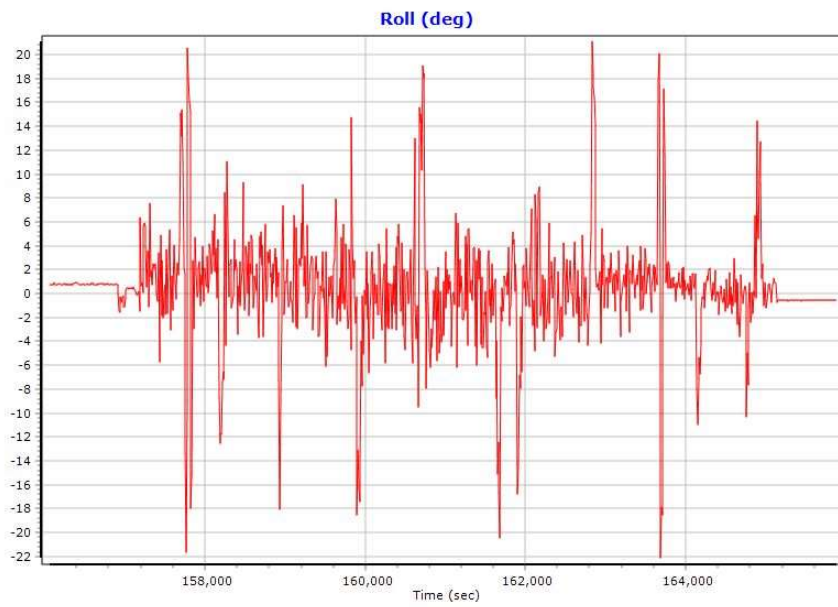
Entire time interval

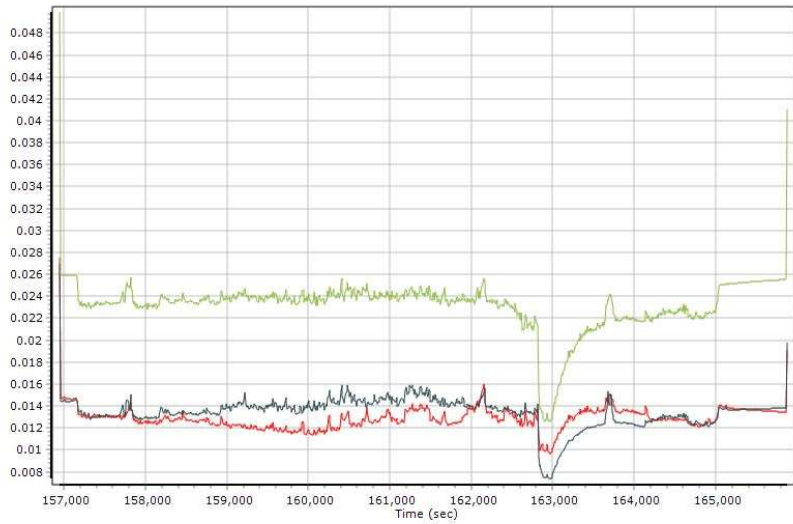
Seconds of start week

UTC Offset: 18.000

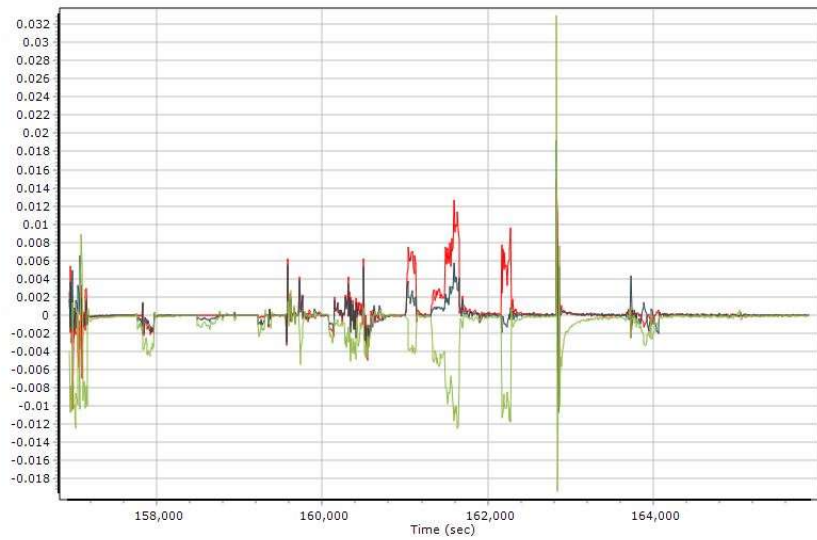
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |



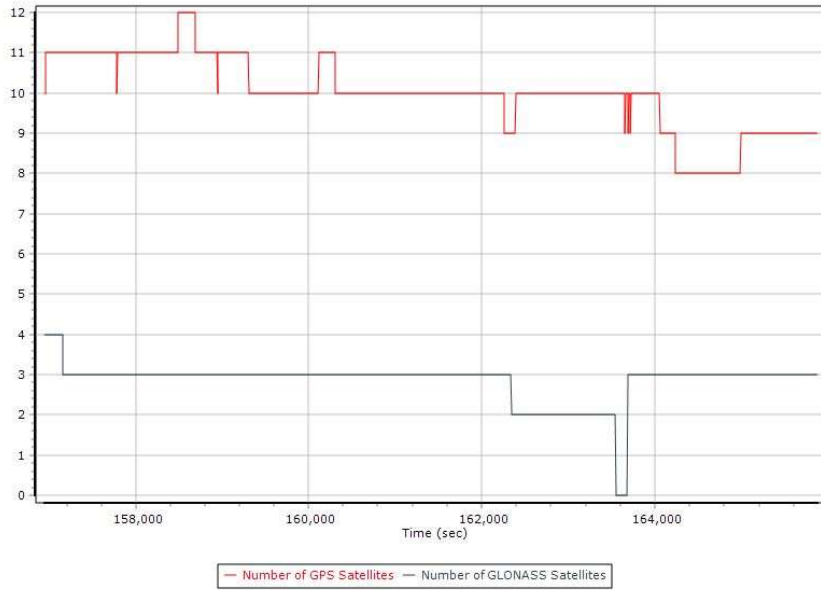




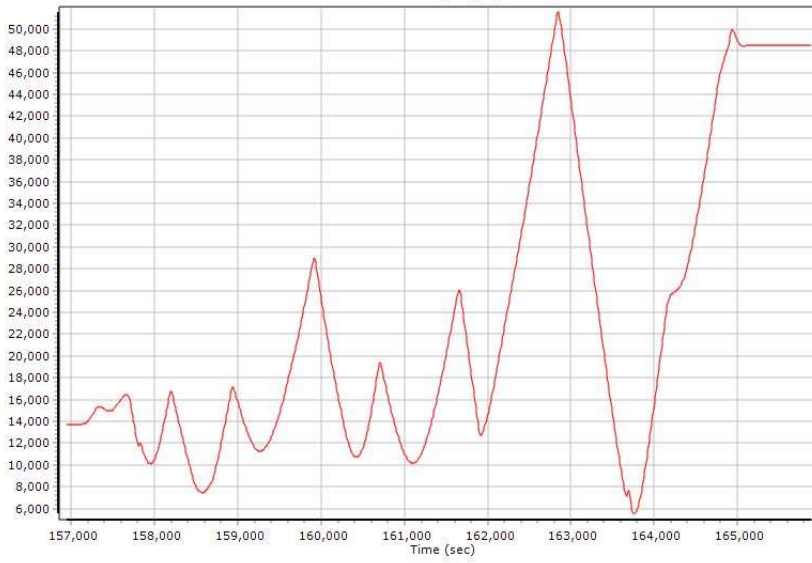
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)

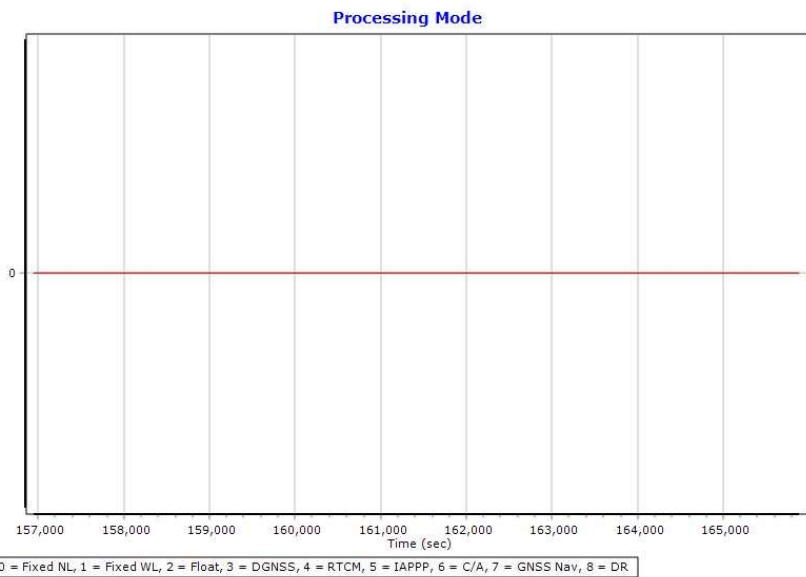
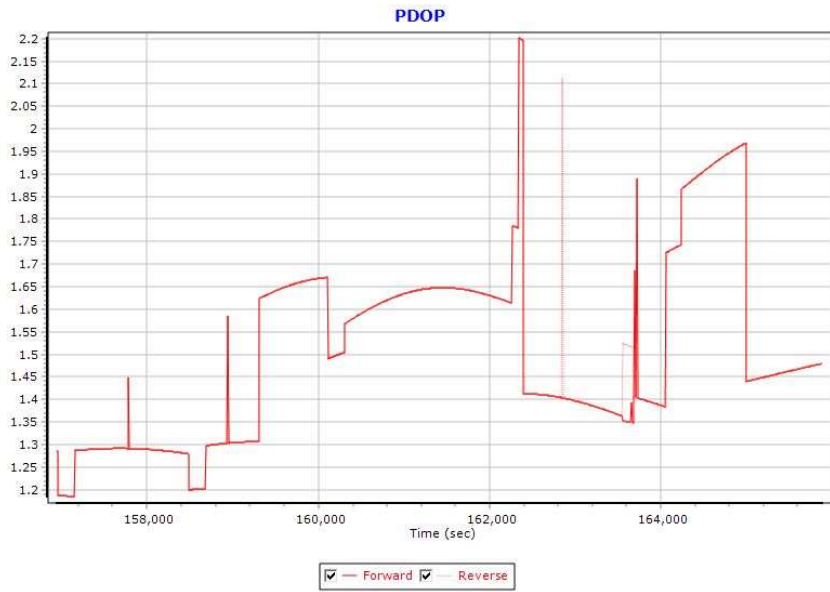


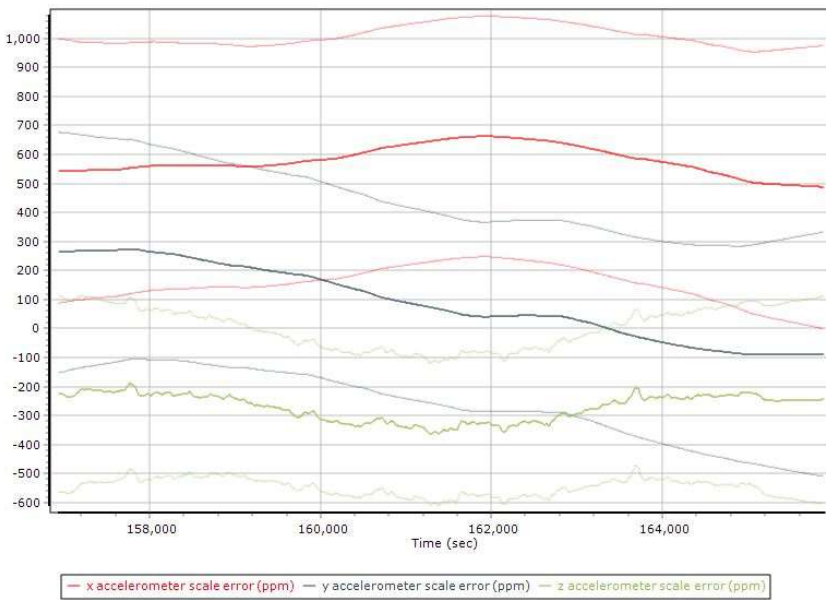
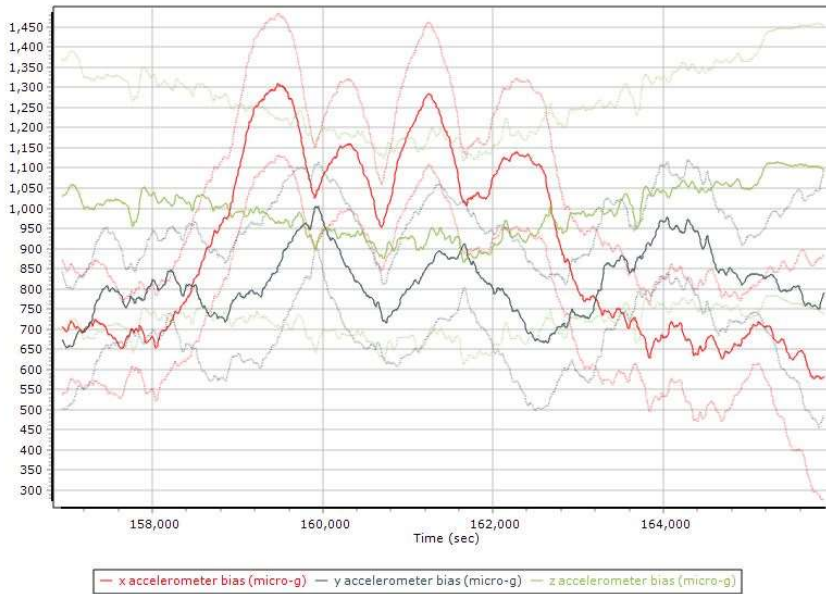
— North (m) — East (m) — Down (m) — DR mode

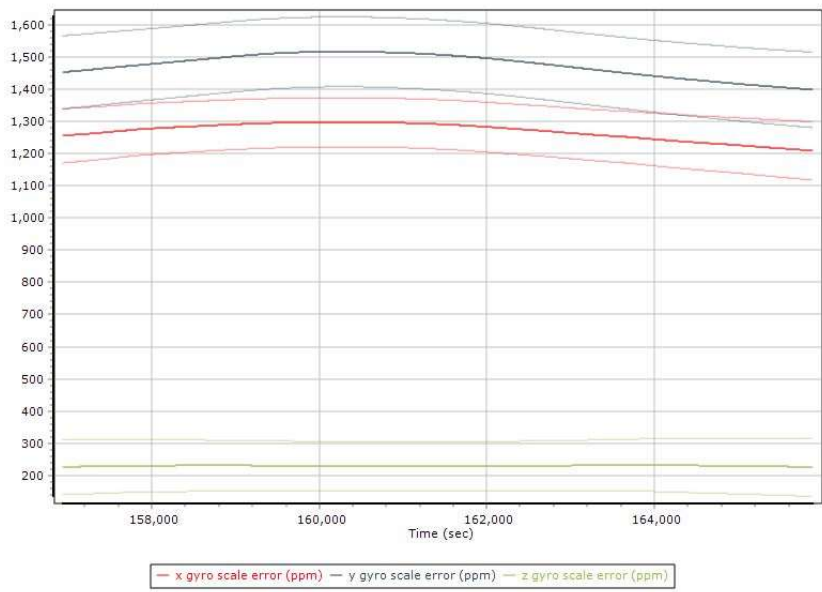
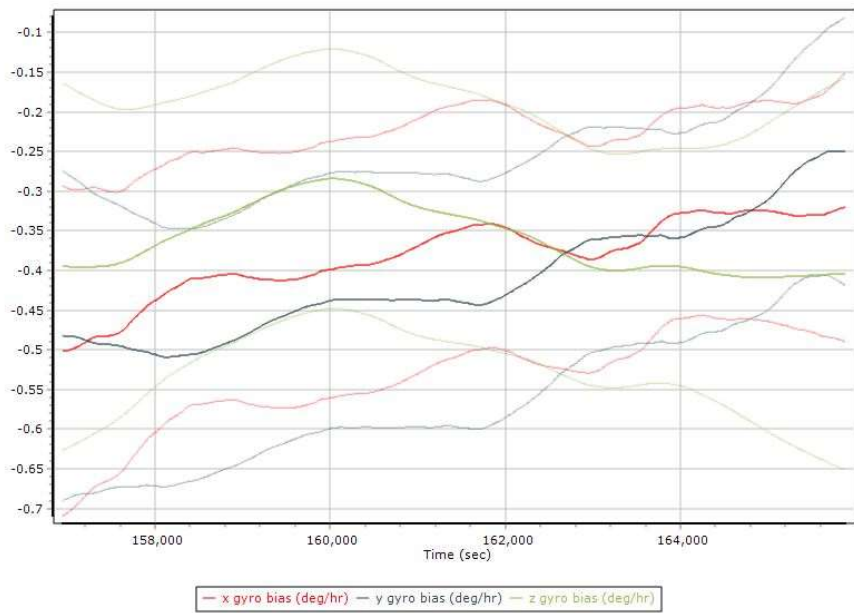


Baseline Length(m)

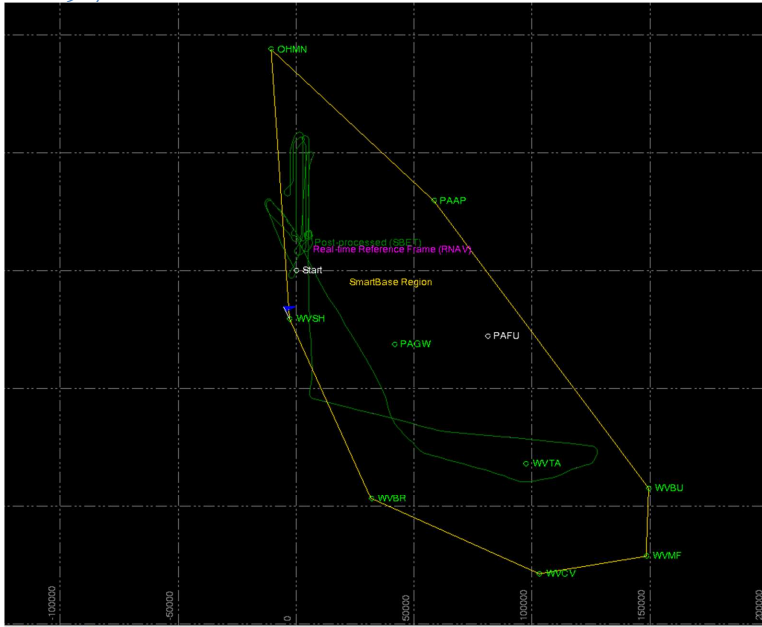








PTG19071A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LIDAR
- SAR

| | | | |
|--------------------------------------------|---------------------------------------|----------------------------------------------|----------------------------------------|
| Stabilized Mount to IMU Lever Arm | | Stabilized Mount to IMU Mounting Angles | |
| X | <input type="text" value="-0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.010 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.352 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Stabilized Mount to Primary GNSS Lever Arm | | Aircraft to Stabilized Mount Mounting Angles | |
| X | <input type="text" value="-0.054 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.140 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.987 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | <input type="text" value="3cm"/> | | |
| | <3cm 10cm 50cm 1m 10m | | |

Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

OK Cancel

Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

Timing

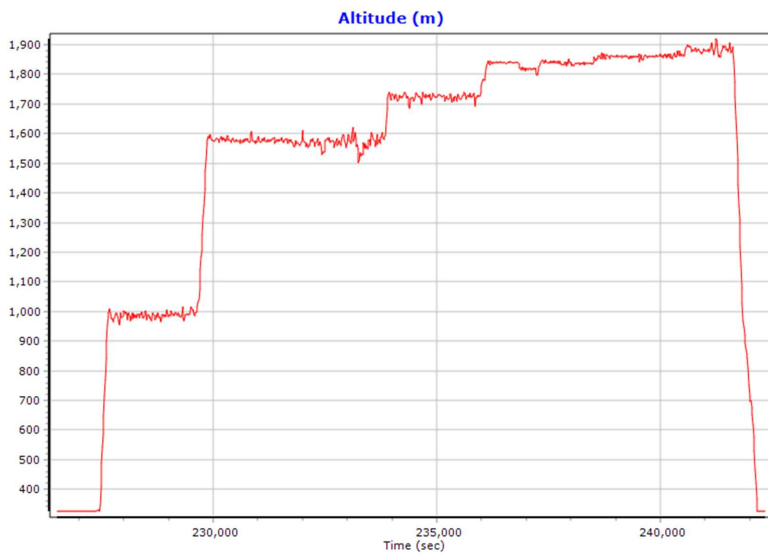
Start: 226498.000
 End: 242351.000

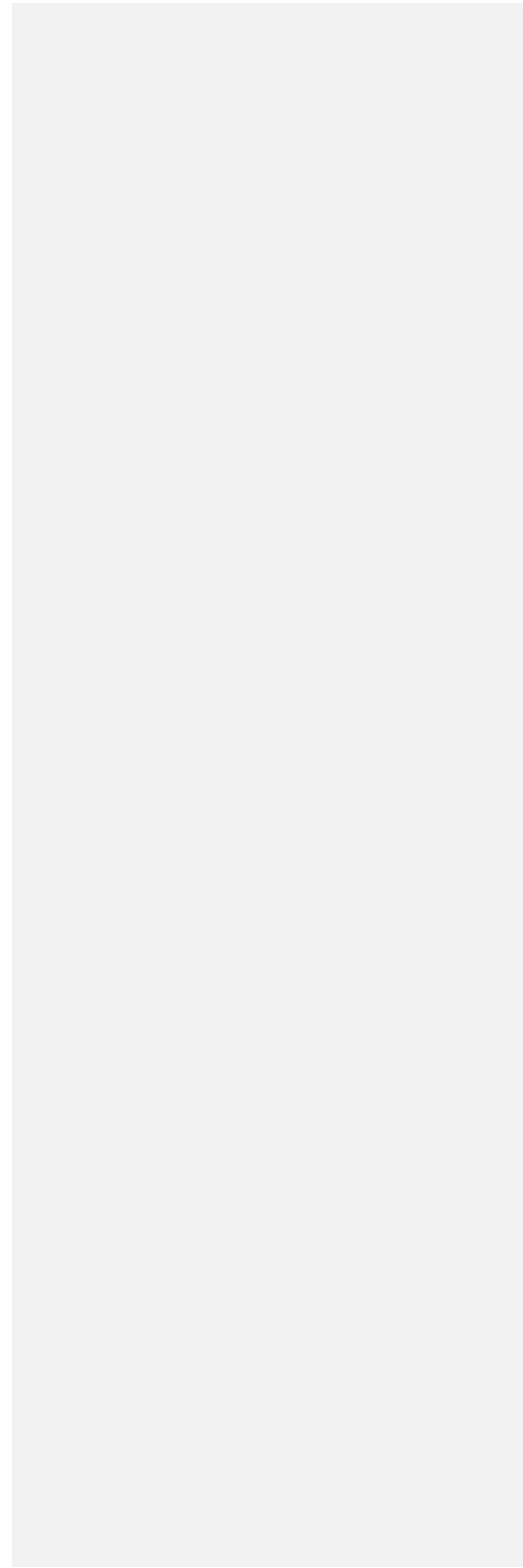
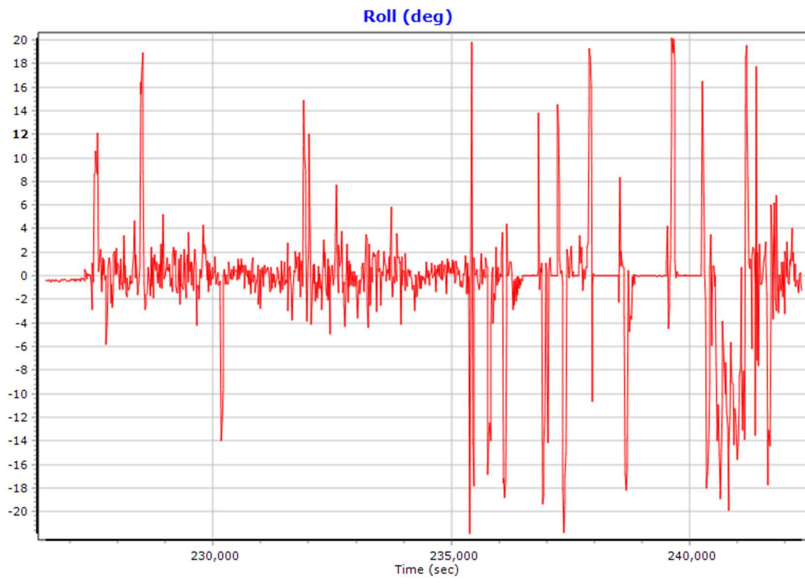
Entire time interval
 Seconds of start week

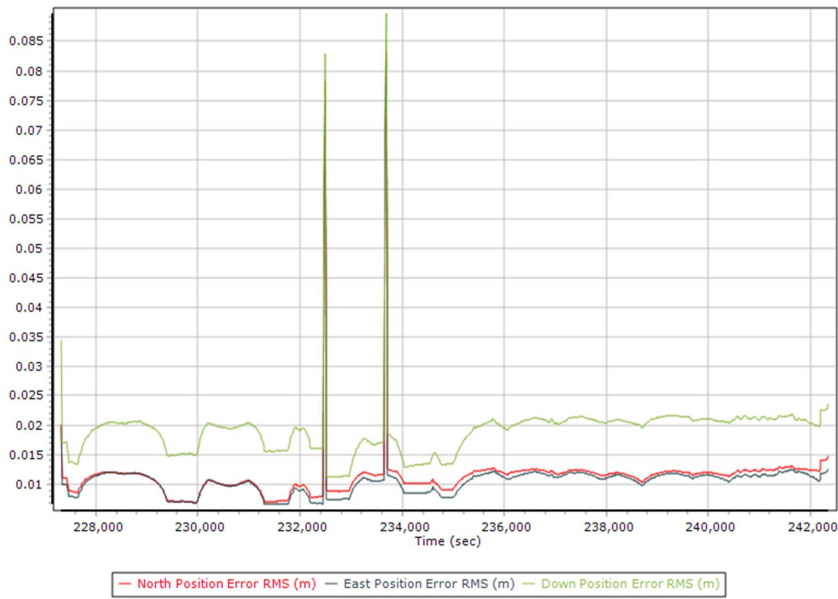
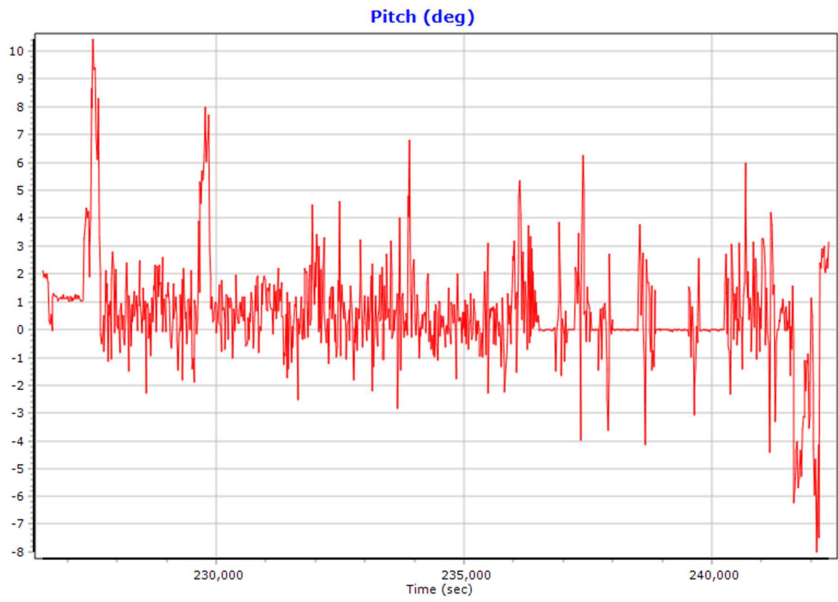
UTC Offset: 18.000

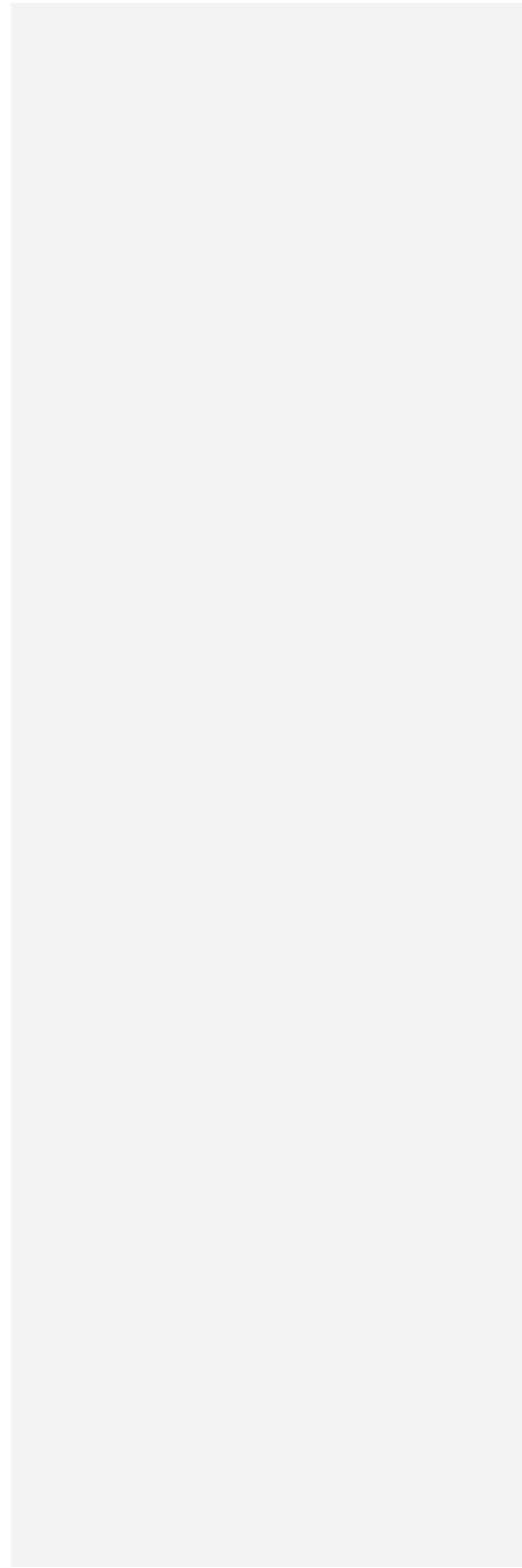
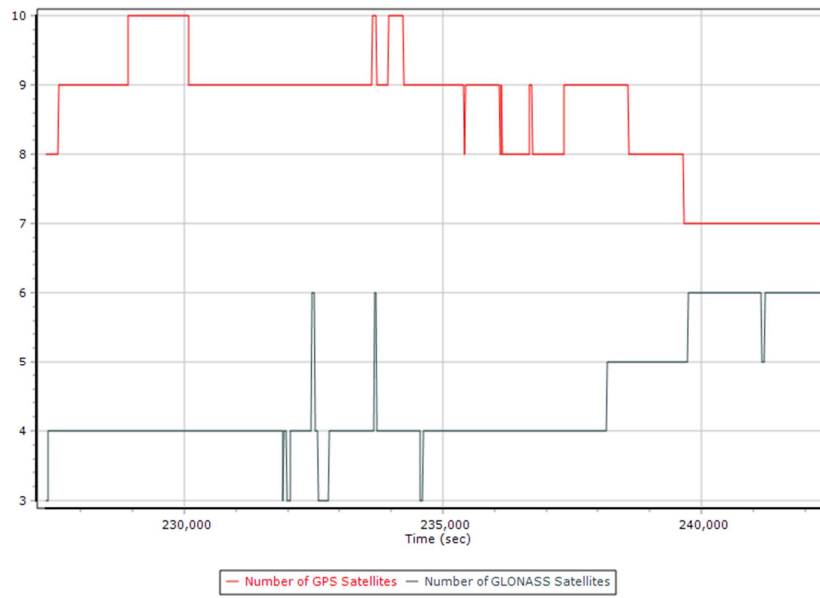
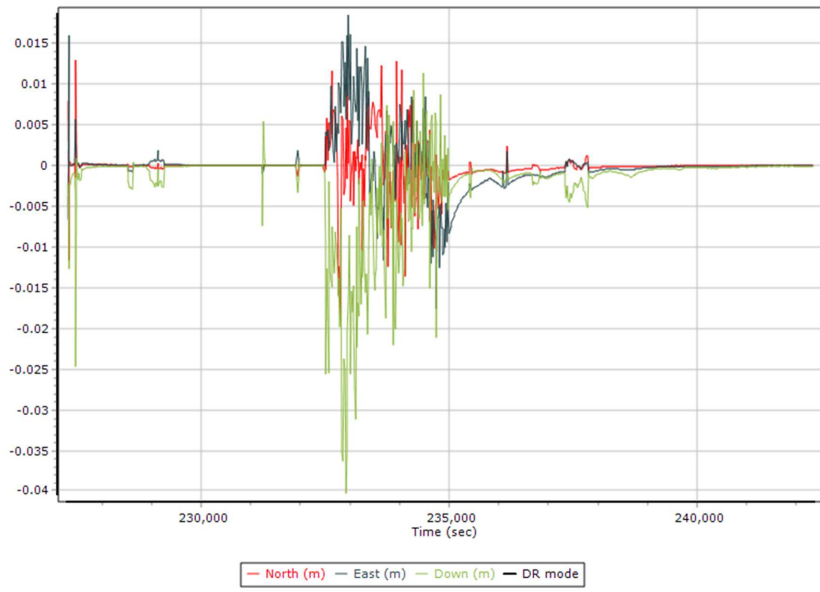
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

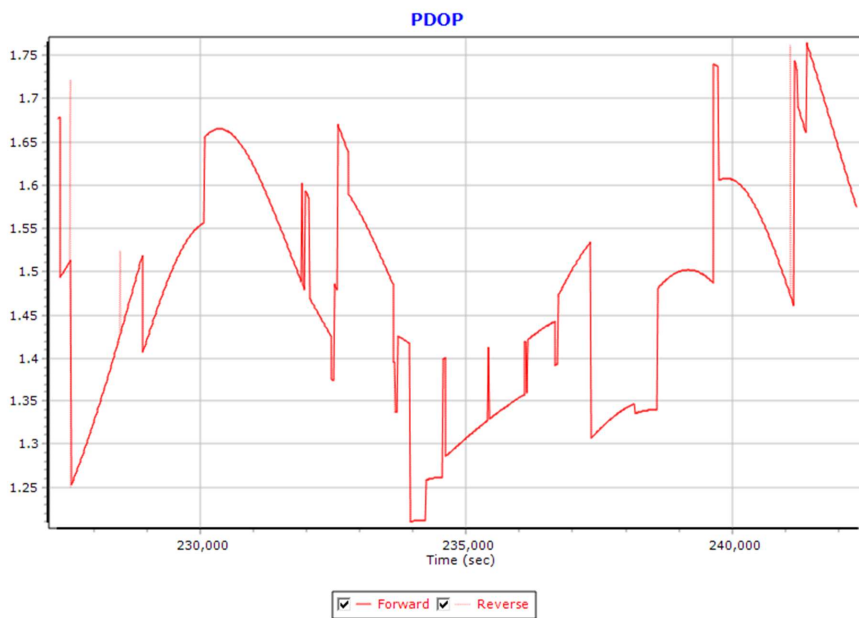
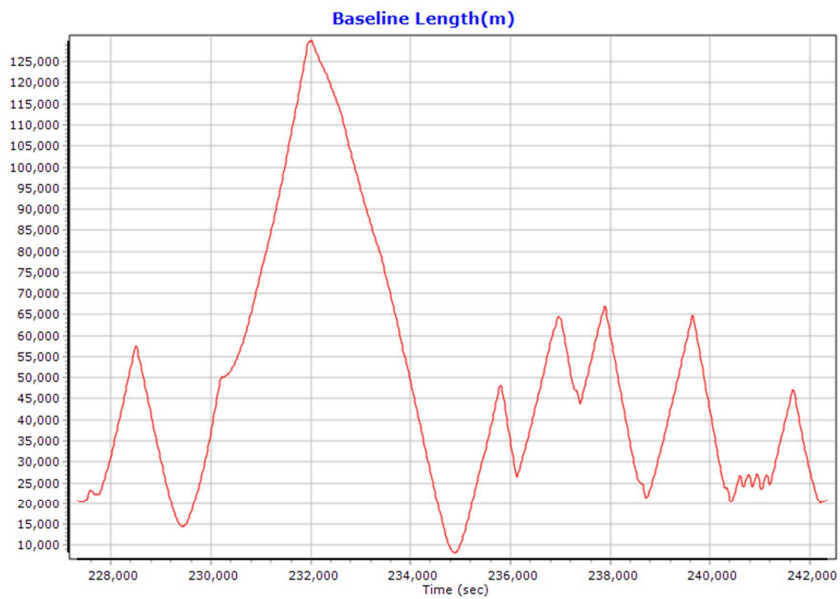
OK Cancel



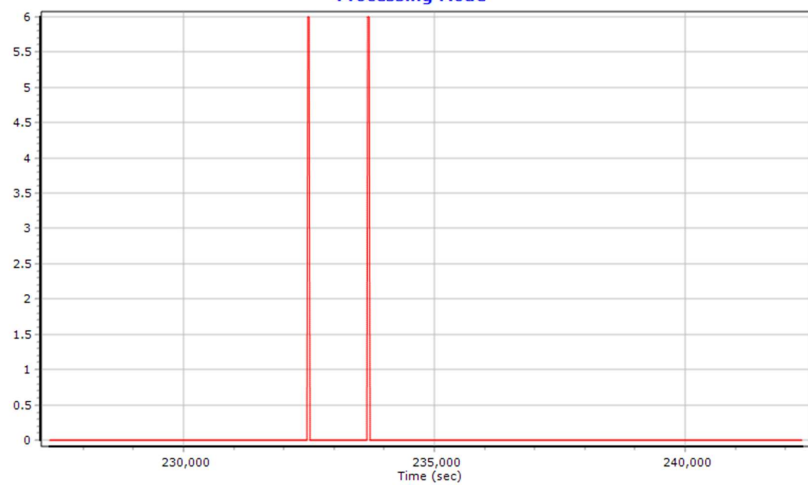






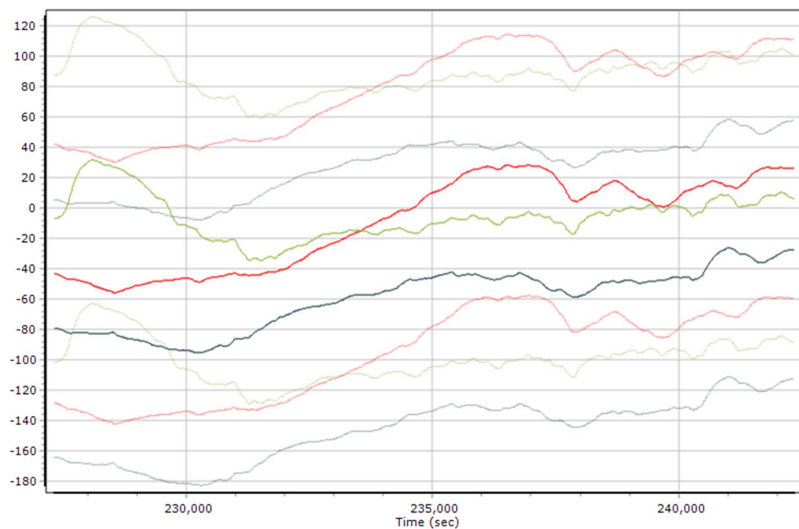


Processing Mode

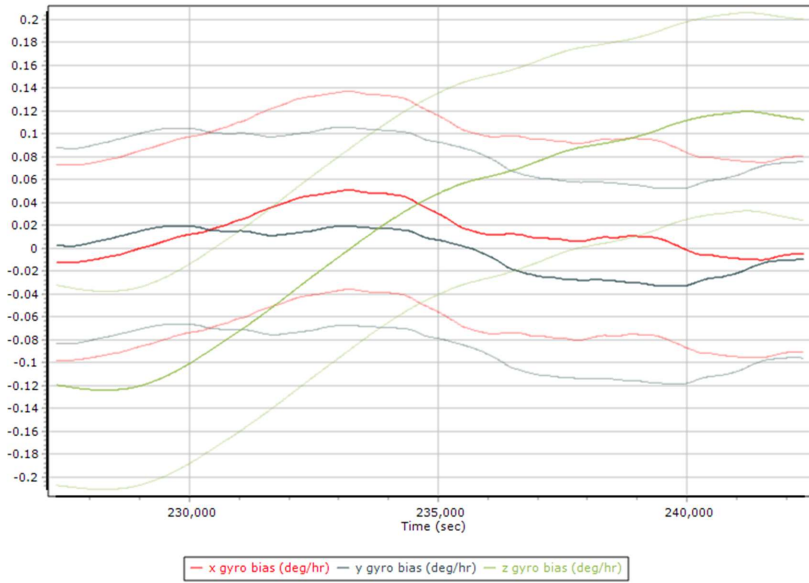
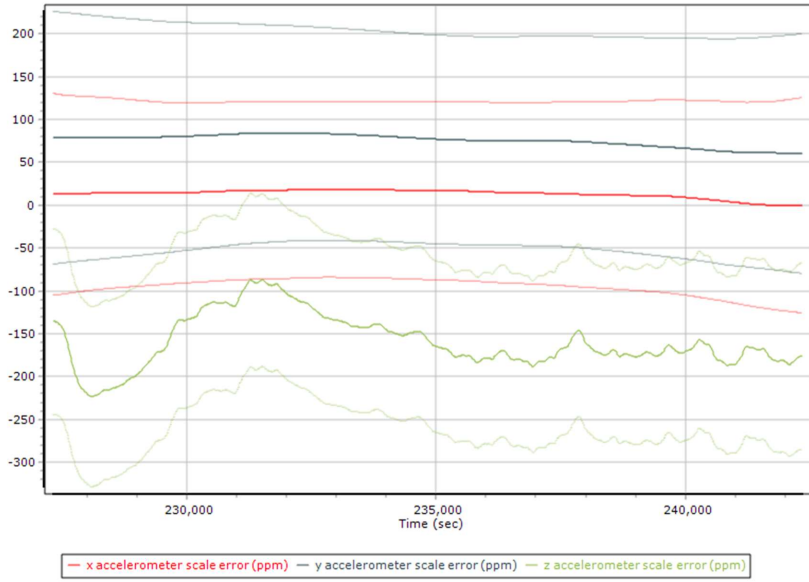


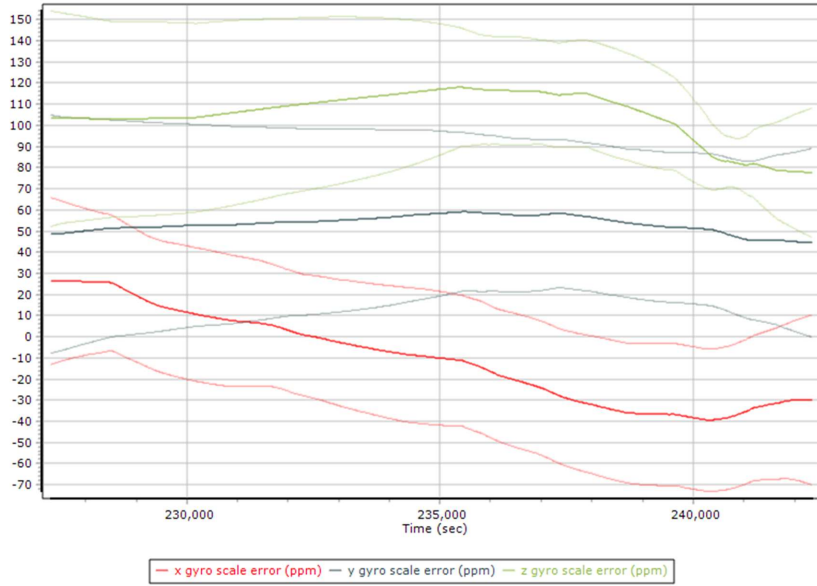
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

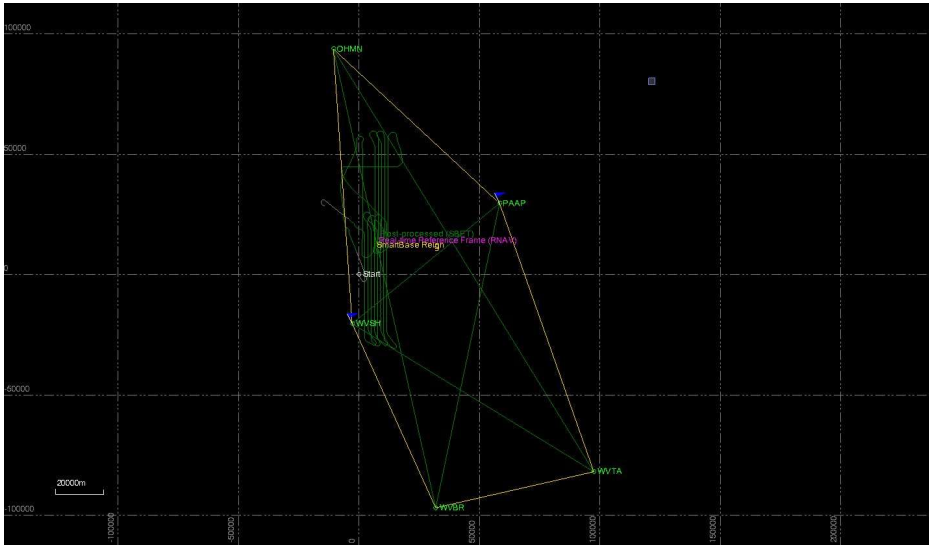


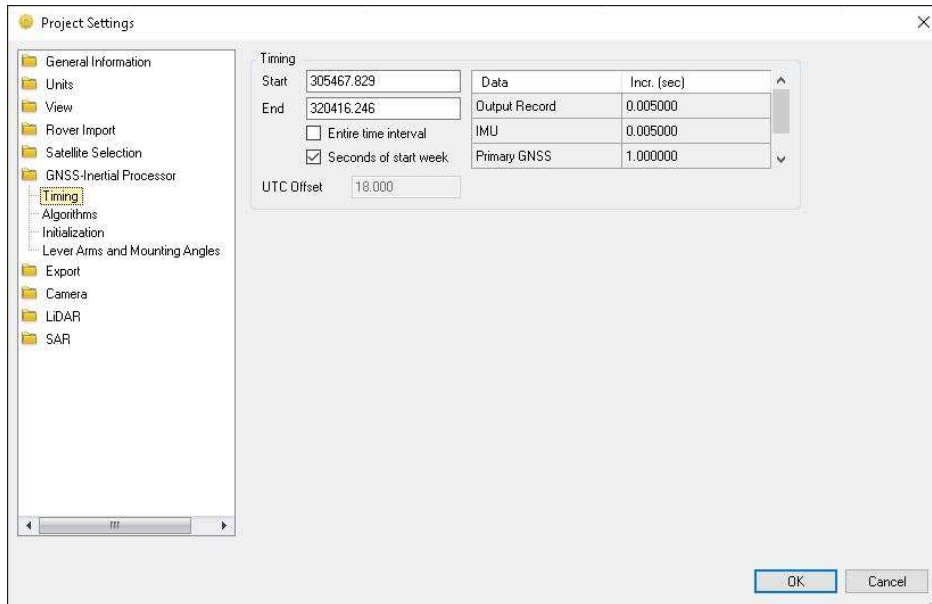
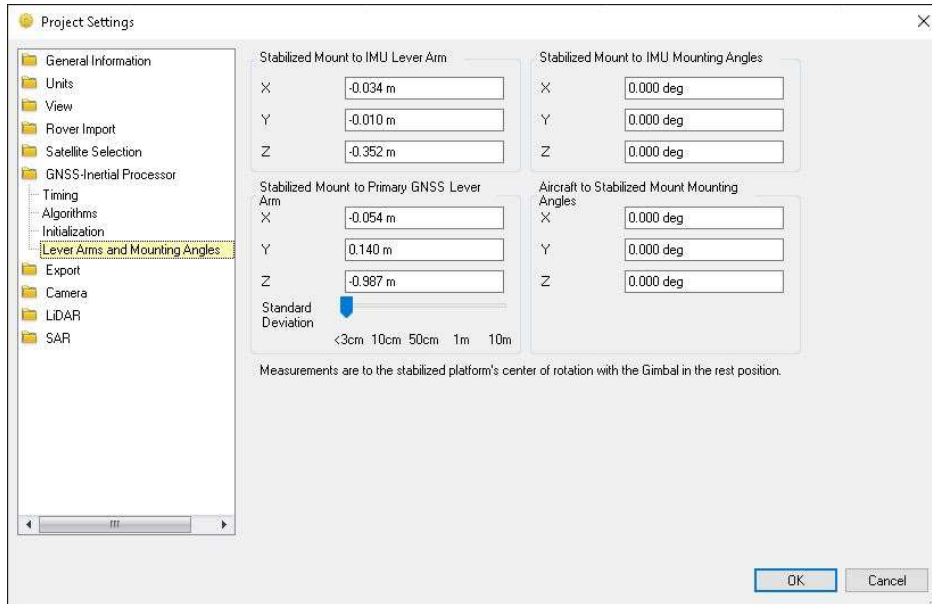
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)

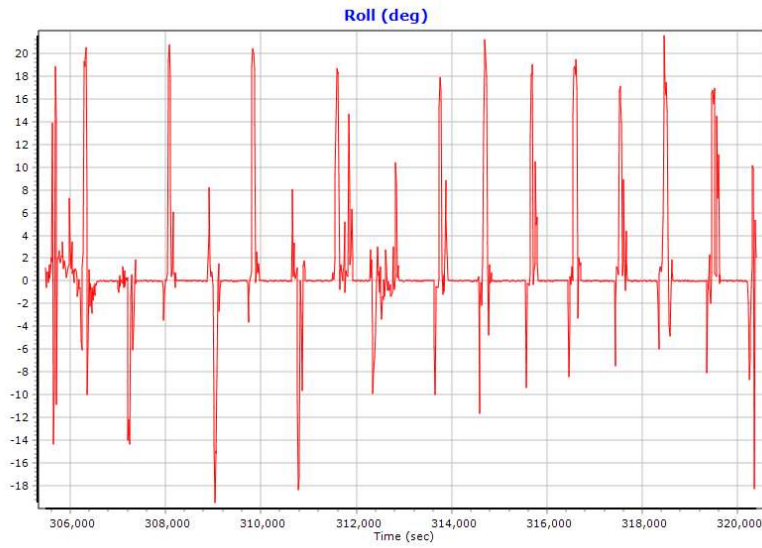
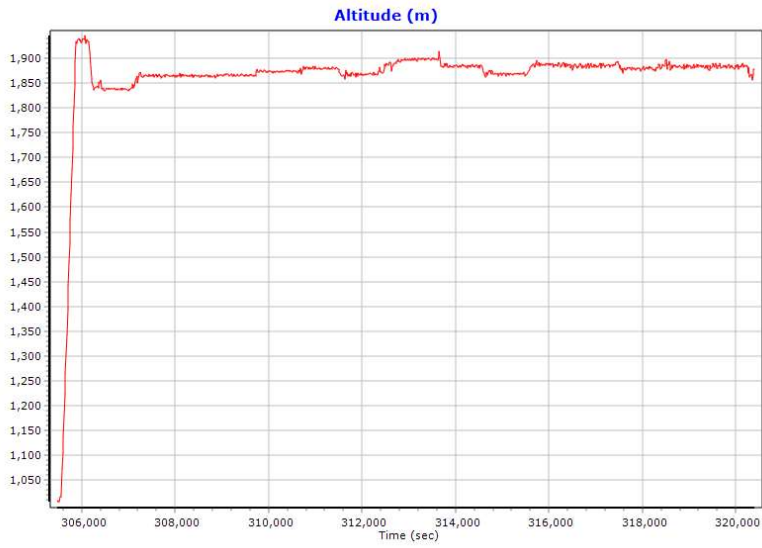




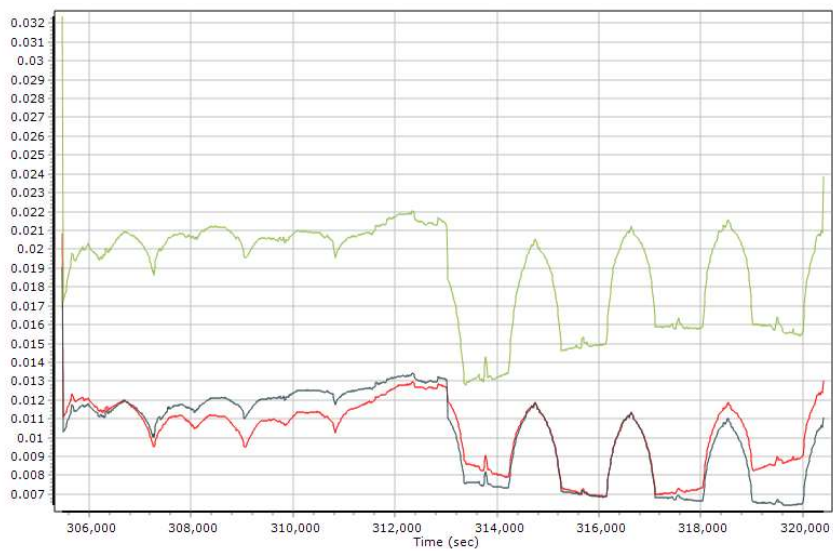
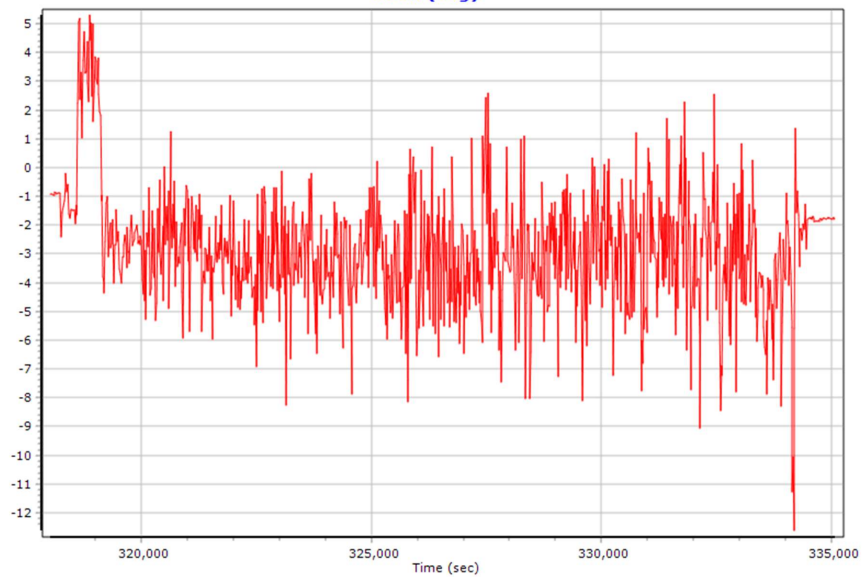
PTG19072A



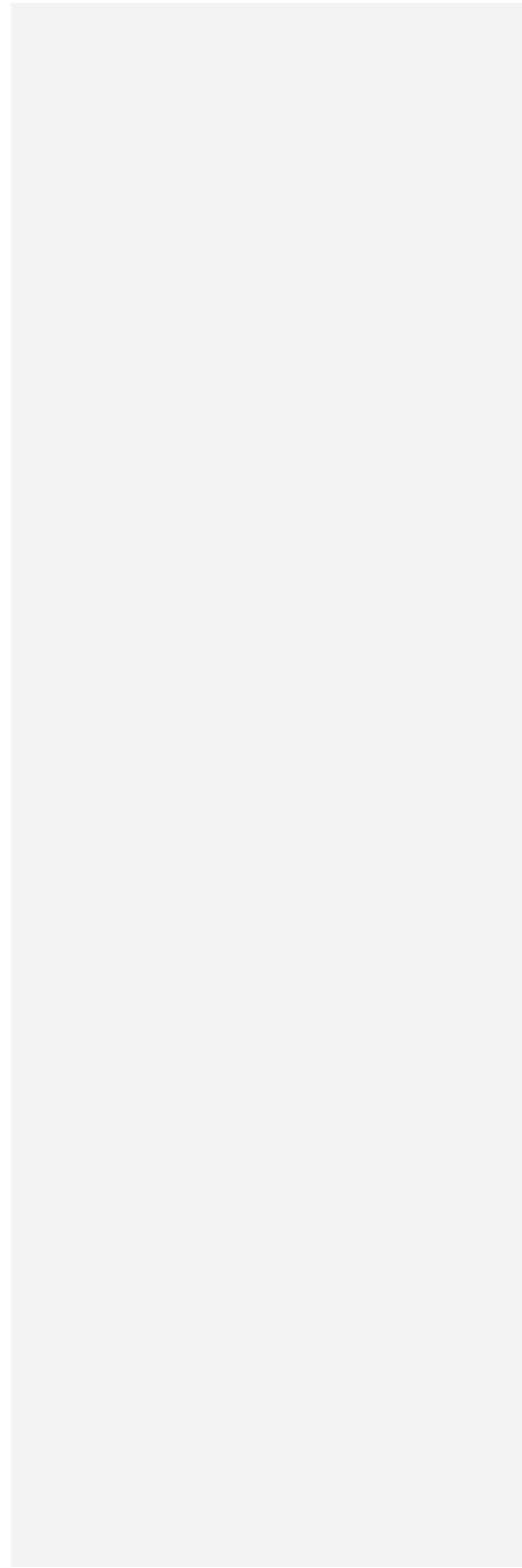
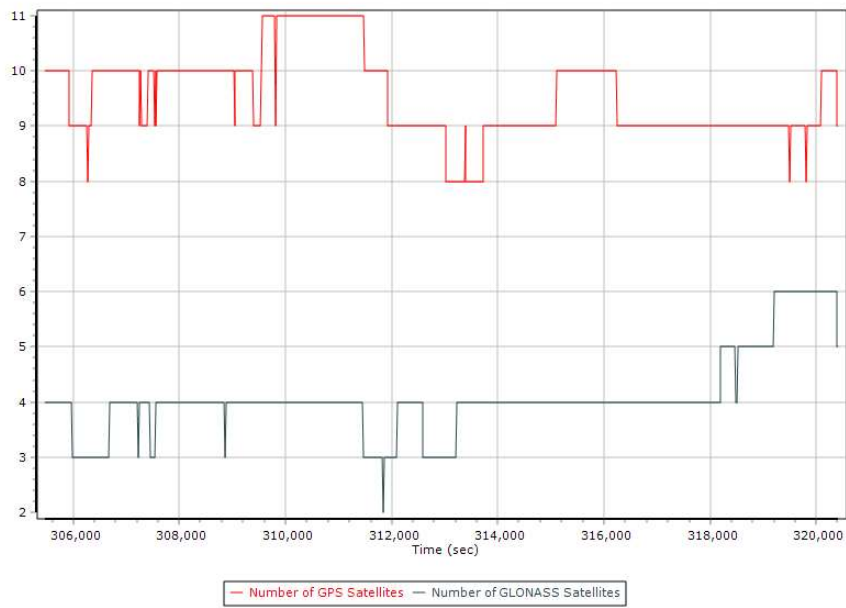
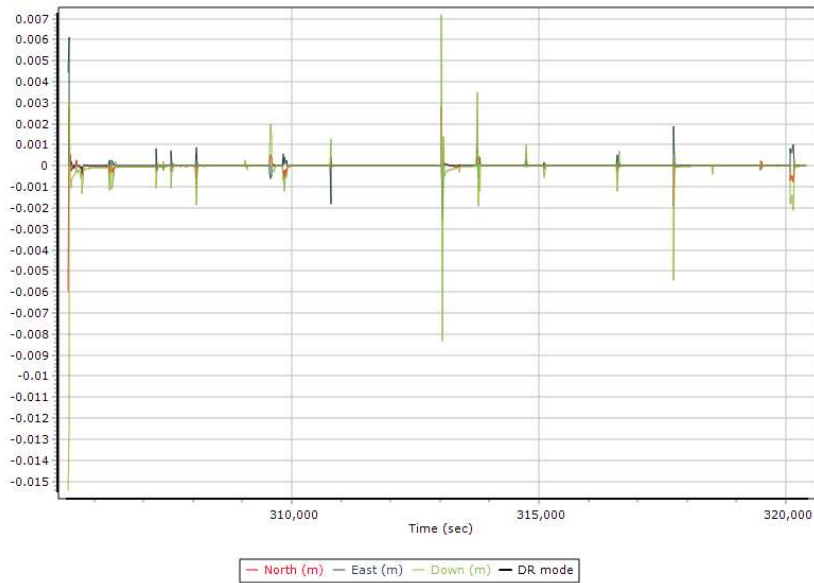


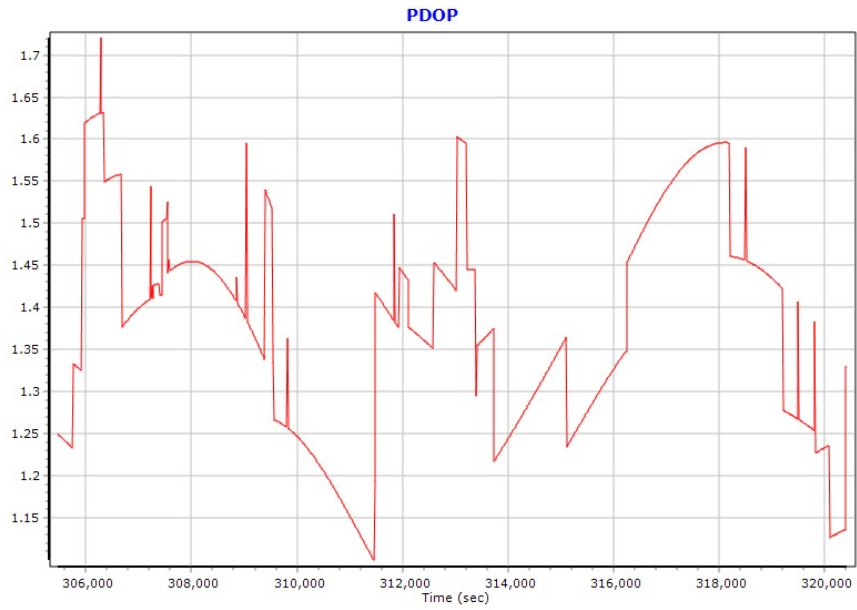
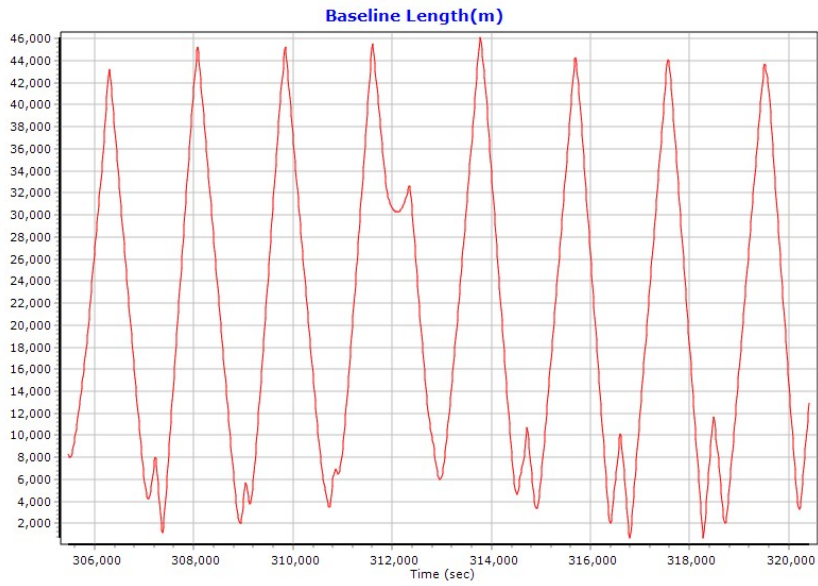


Pitch (deg)

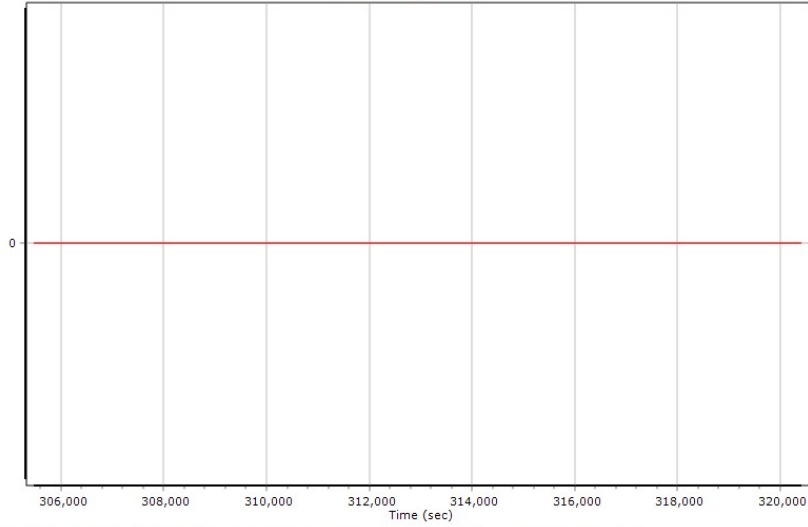


— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)

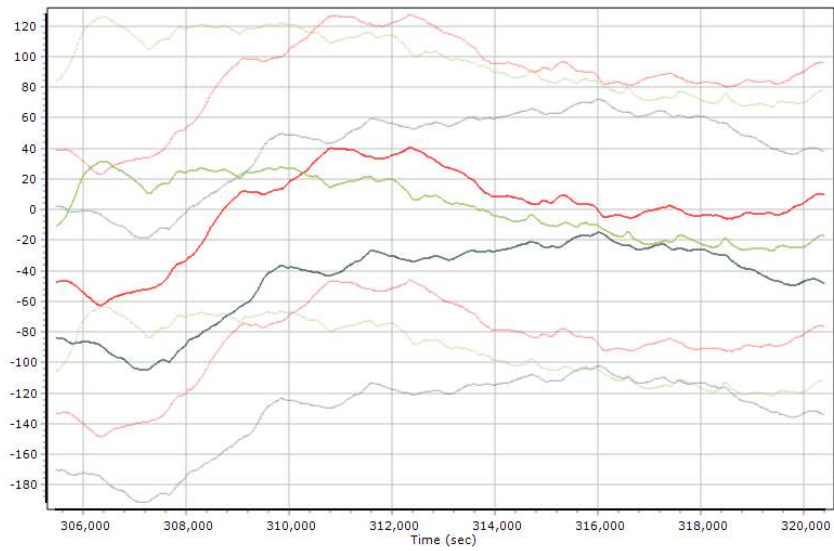




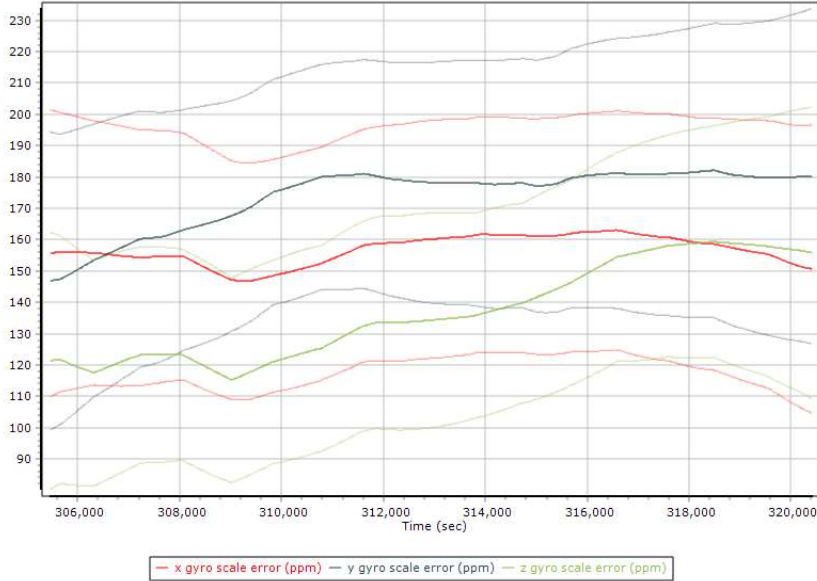
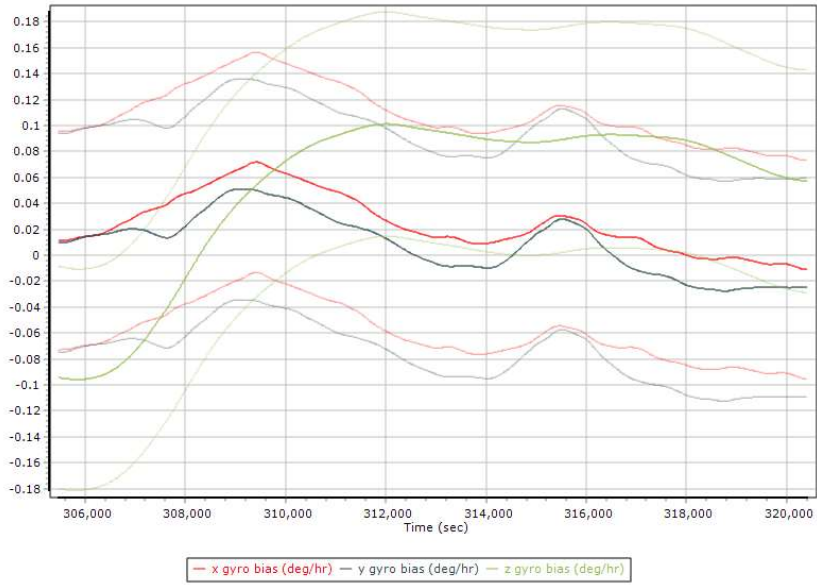
Processing Mode



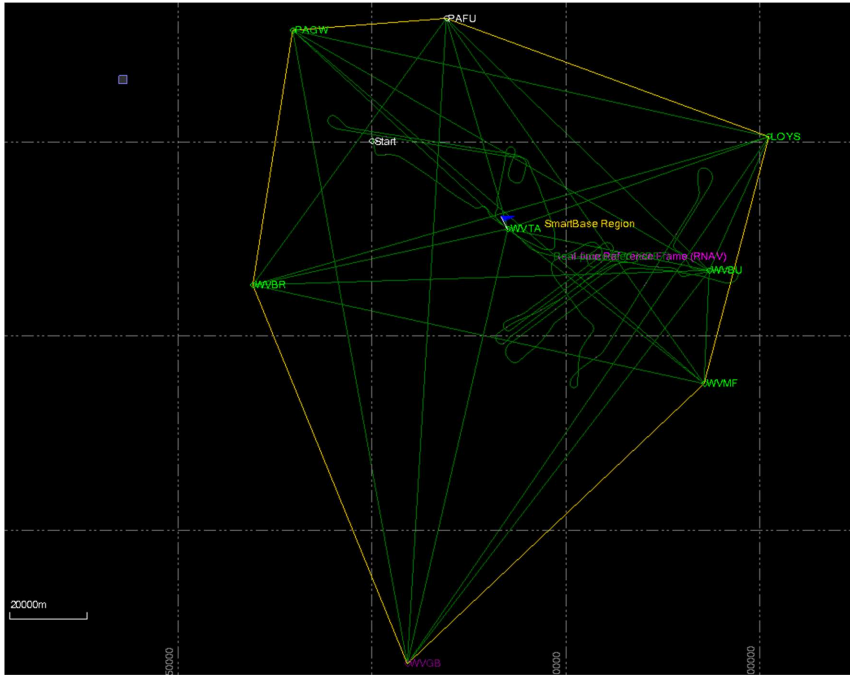
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



PTG19091A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

| Stabilized Mount to IMU Lever Arm | | Stabilized Mount to IMU Mounting Angles | |
|--------------------------------------------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|----------------------------------------------|-----------|
| X | -0.034 m | X | 0.000 deg |
| Y | -0.010 m | Y | 0.000 deg |
| Z | -0.352 m | Z | 0.000 deg |
| Stabilized Mount to Primary GNSS Lever Arm | | Aircraft to Stabilized Mount Mounting Angles | |
| X | -0.054 m | X | 0.000 deg |
| Y | 0.140 m | Y | 0.000 deg |
| Z | -0.987 m | Z | 0.000 deg |
| Standard Deviation | <input type="button" value="3cm"/> <input type="button" value="10cm"/> <input type="button" value="50cm"/> <input type="button" value="1m"/> <input type="button" value="10m"/> | | |

Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

Project Settings

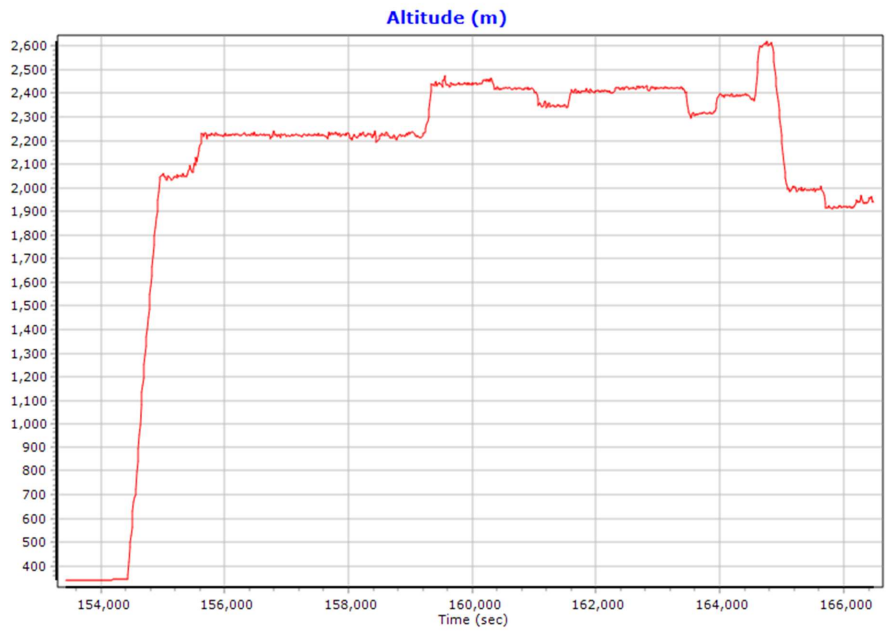
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
Timing
Algorithms
Initialization

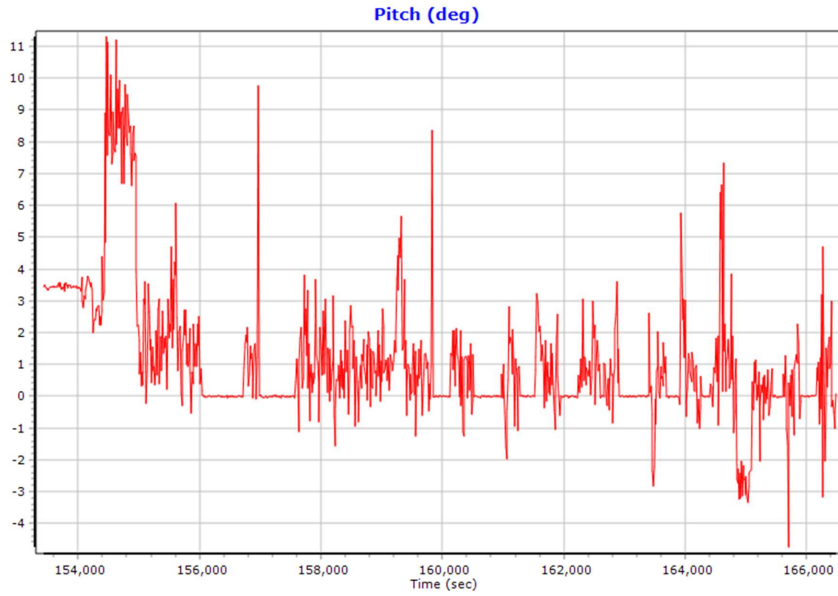
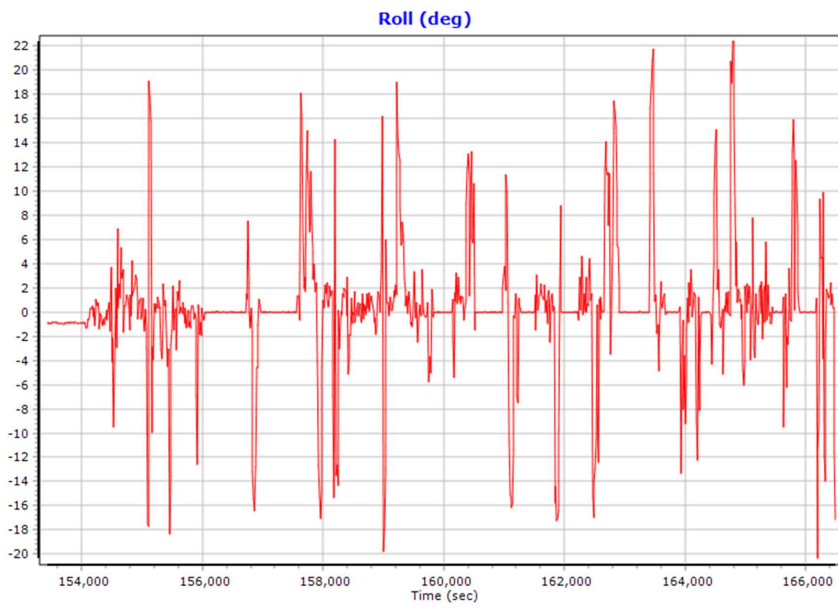
Timing

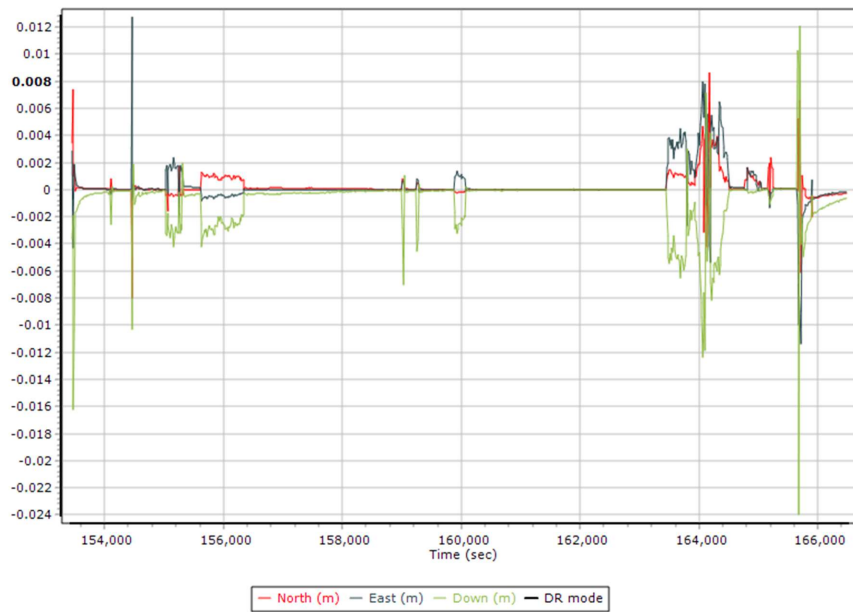
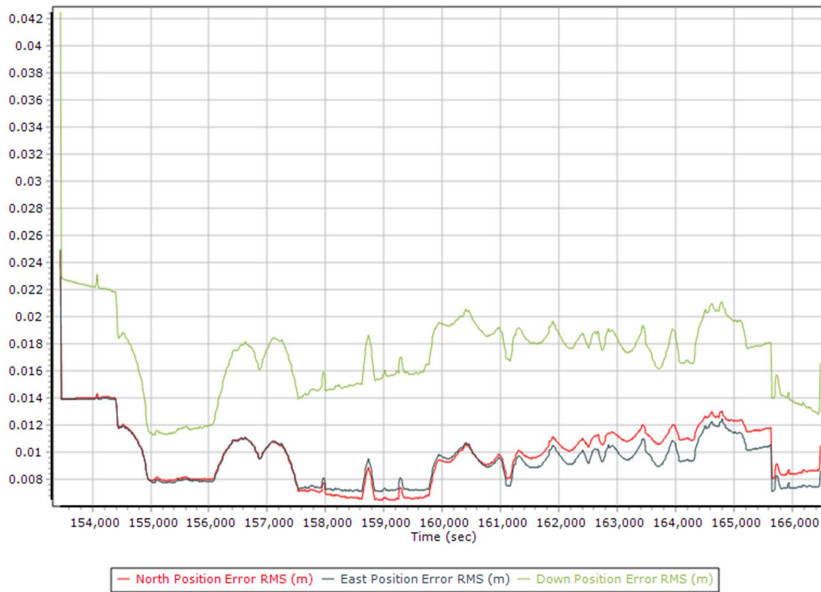
Start: 153430.029
End: 166488.000
UTC Offset: 18.000

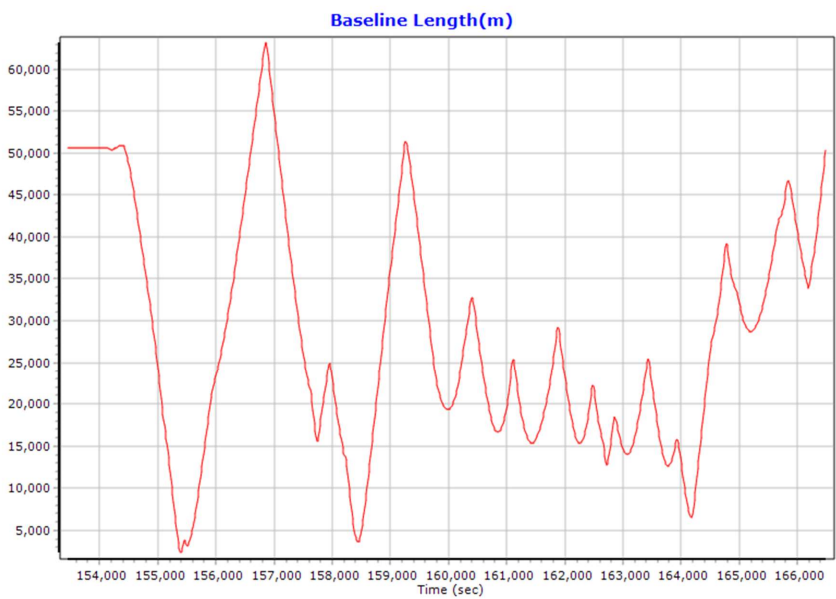
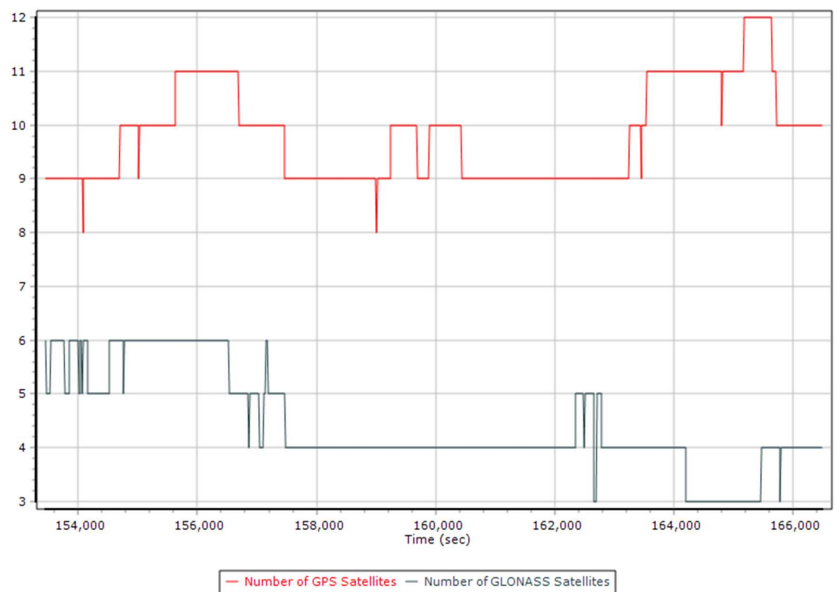
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

Entire time interval
 Seconds of start week

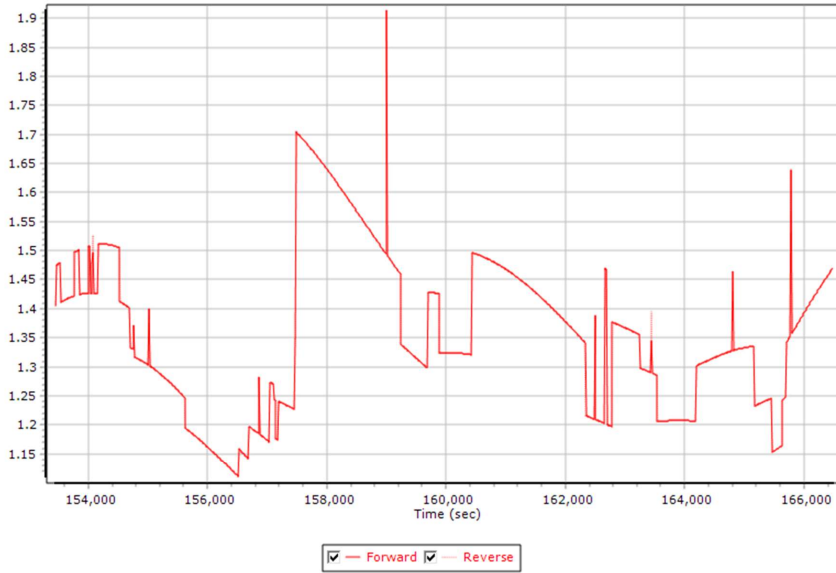




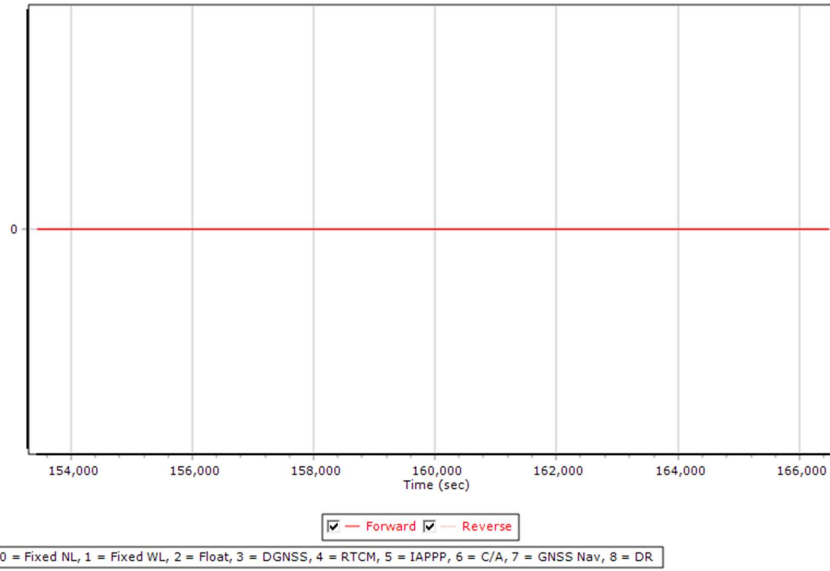


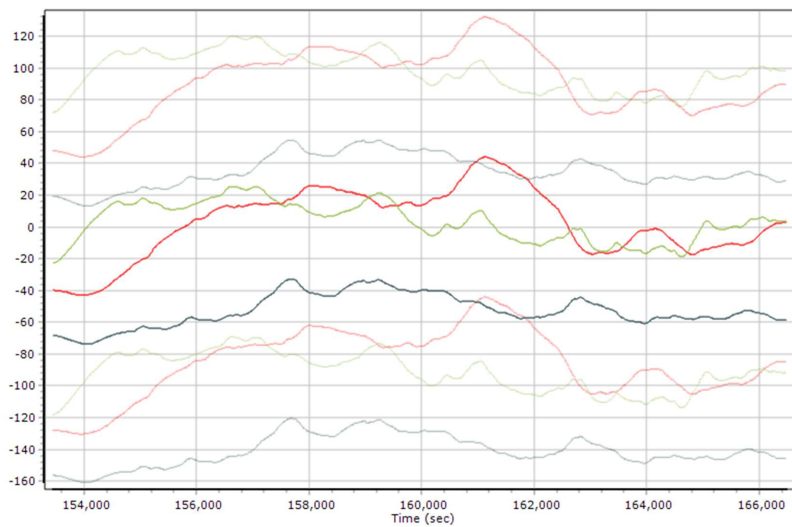


PDOP

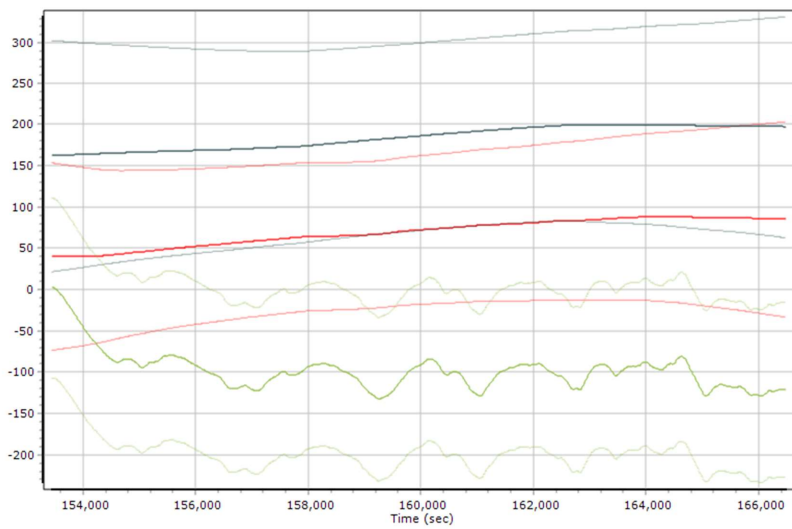


Processing Mode

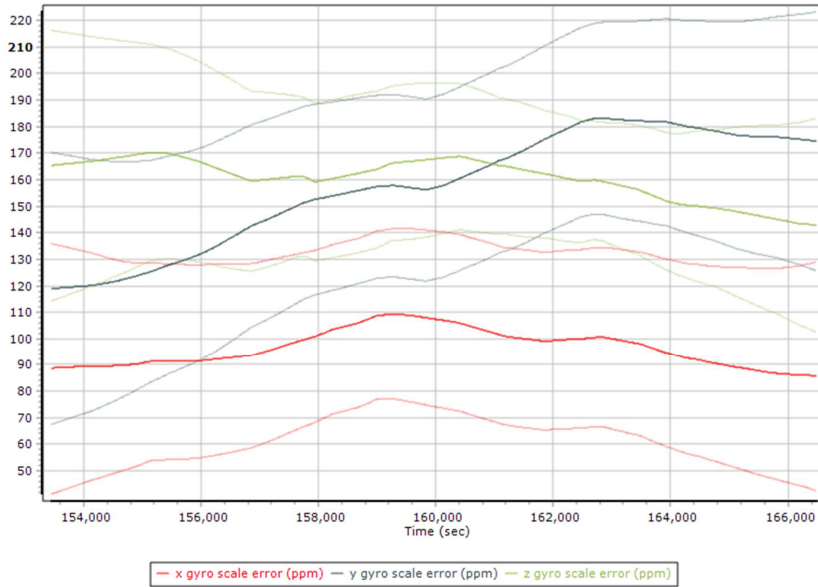
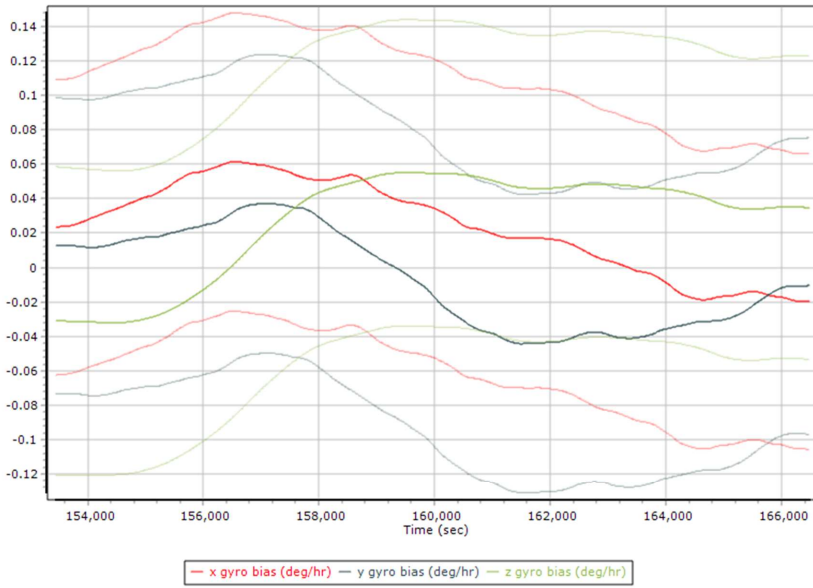




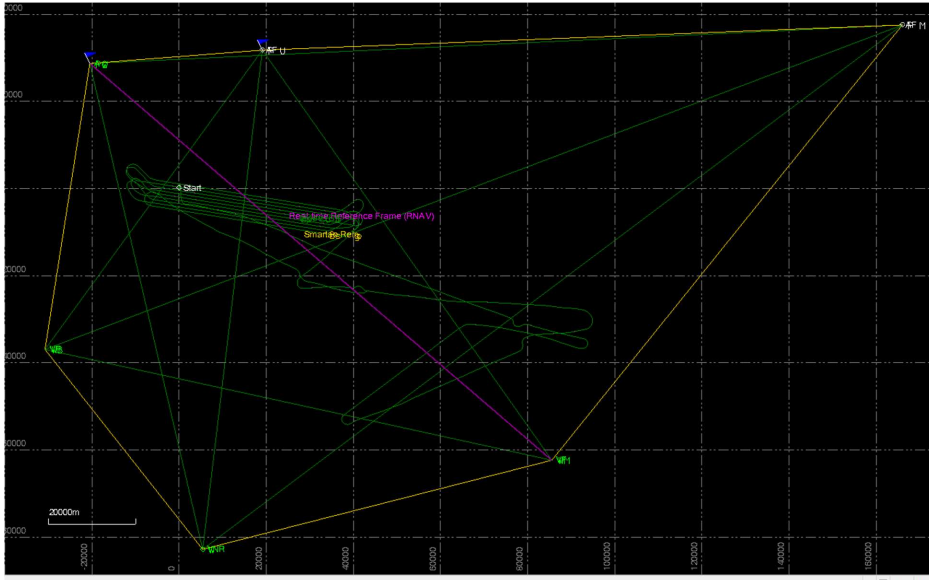
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



PTG19092A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

| Stabilized Mount to IMU Lever Arm | Stabilized Mount to IMU Mounting Angles |
|-----------------------------------|-----------------------------------------|
| X: -0.034 m | X: 0.000 deg |
| Y: -0.010 m | Y: 0.000 deg |
| Z: -0.352 m | Z: 0.000 deg |

| Stabilized Mount to Primary GNSS Lever Arm | Aircraft to Stabilized Mount Mounting Angles |
|--------------------------------------------|----------------------------------------------|
| X: -0.054 m | X: 0.000 deg |
| Y: 0.140 m | Y: 0.000 deg |
| Z: -0.987 m | Z: 0.000 deg |

Standard Deviation: <3cm 10cm 50cm 1m 10m

Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

OK Cancel

Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

Timing

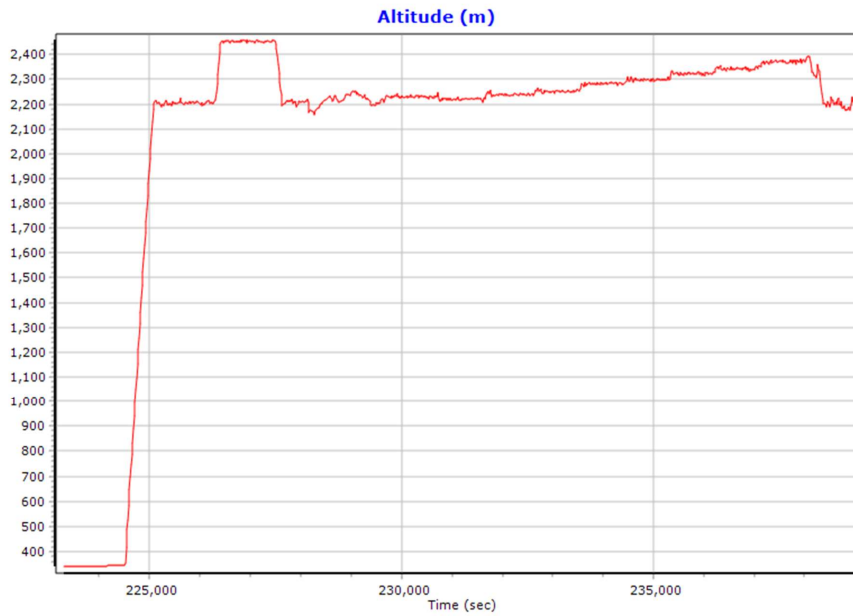
Start: 223301.000
 End: 238961.000

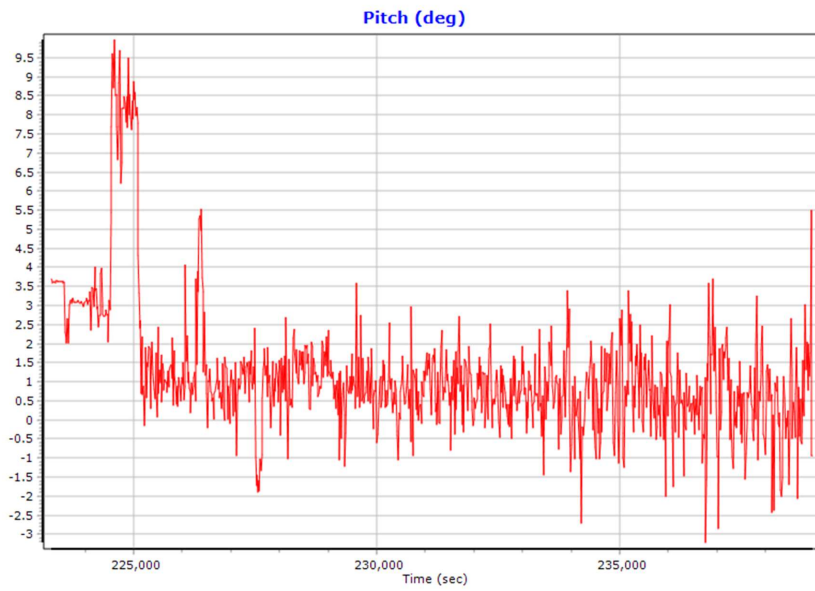
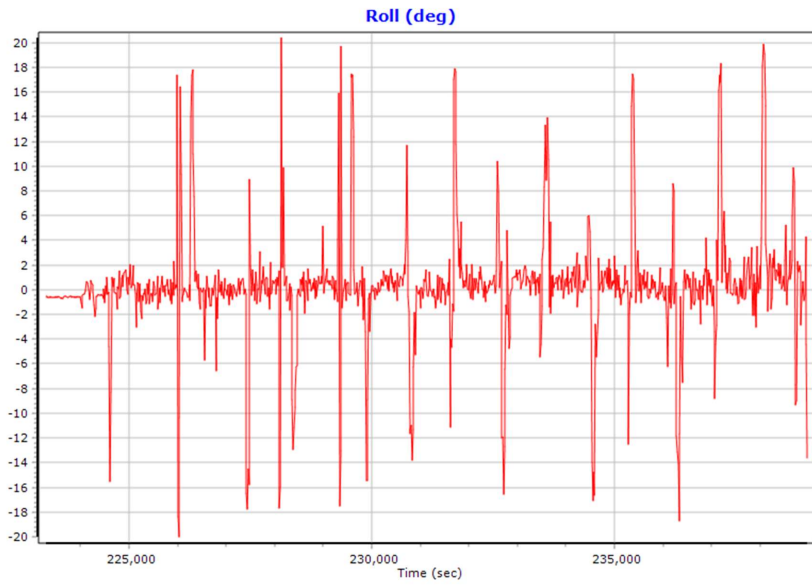
Entire time interval
 Seconds of start week

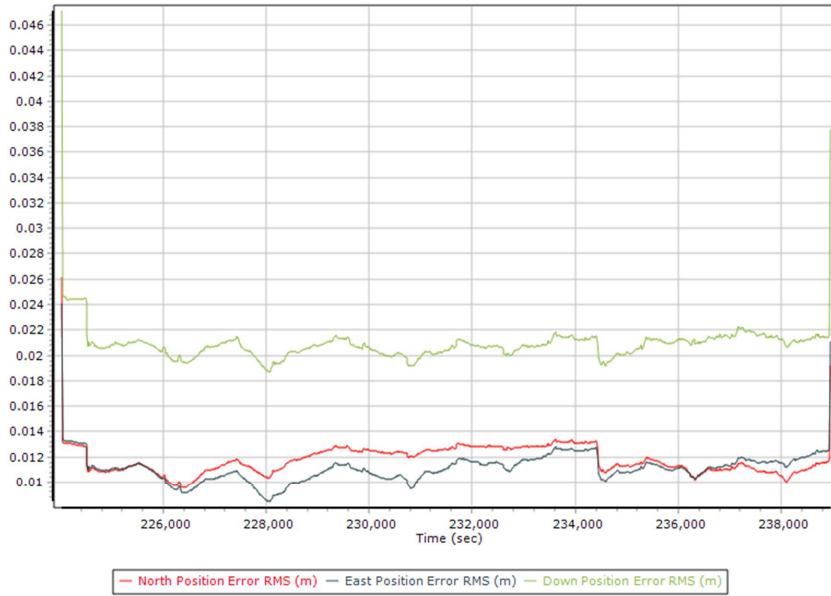
UTC Offset: 18.000

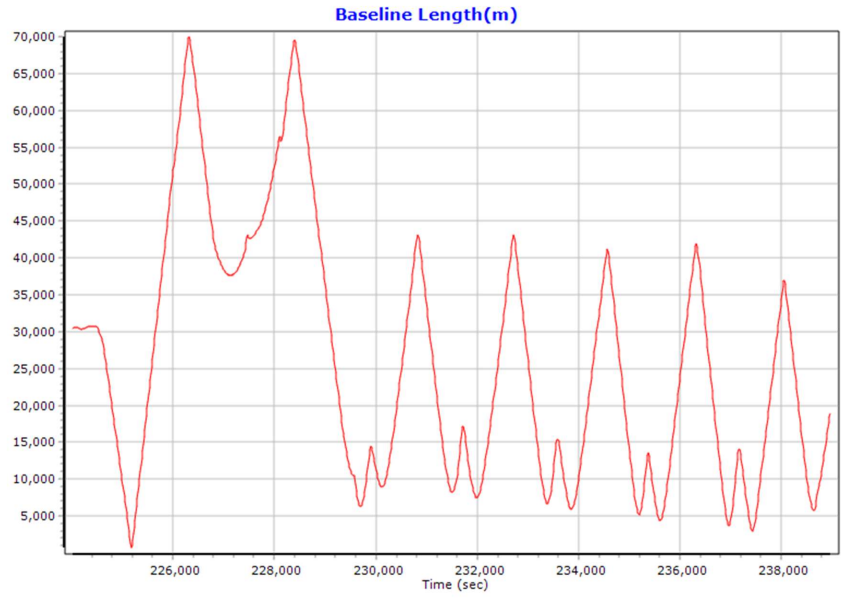
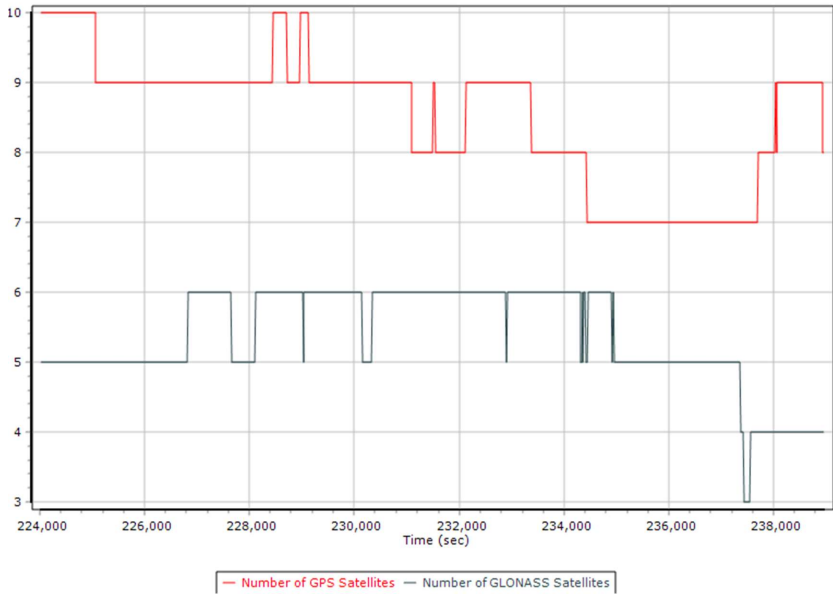
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

OK Cancel

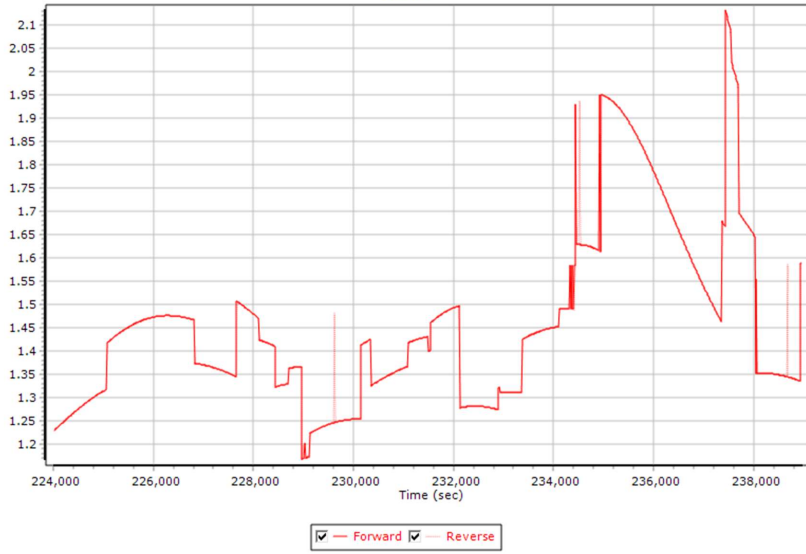






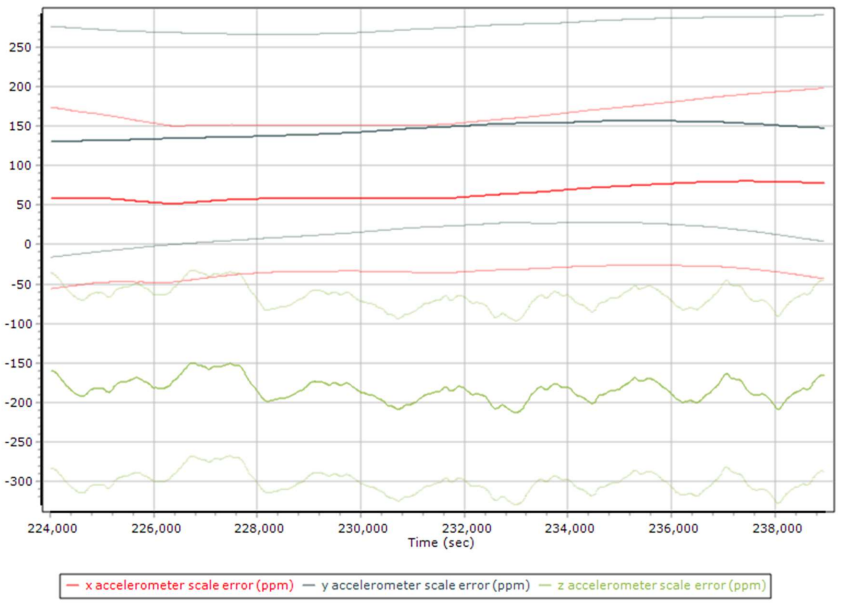
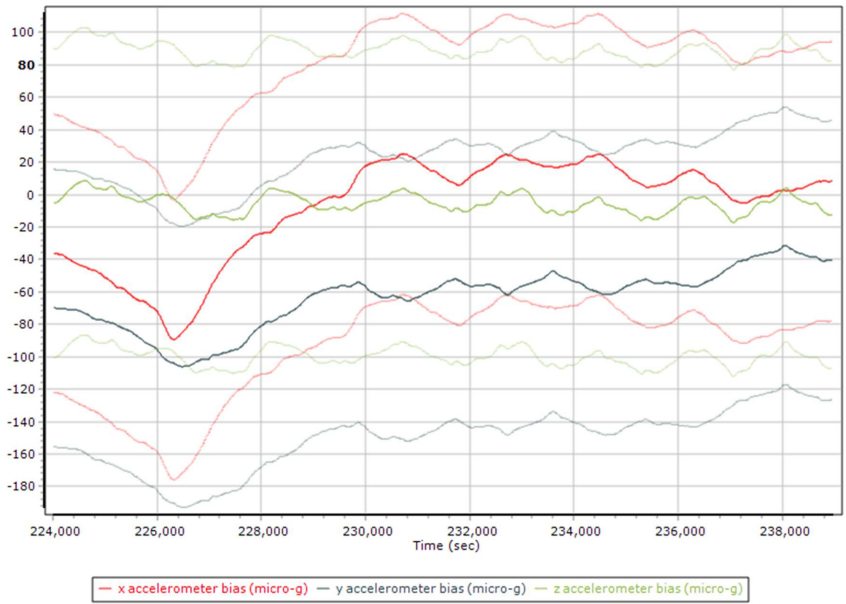


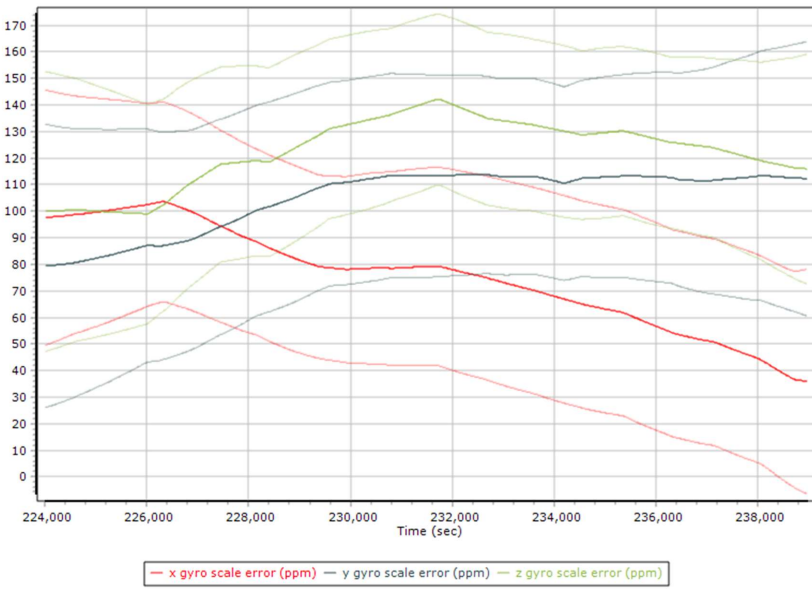
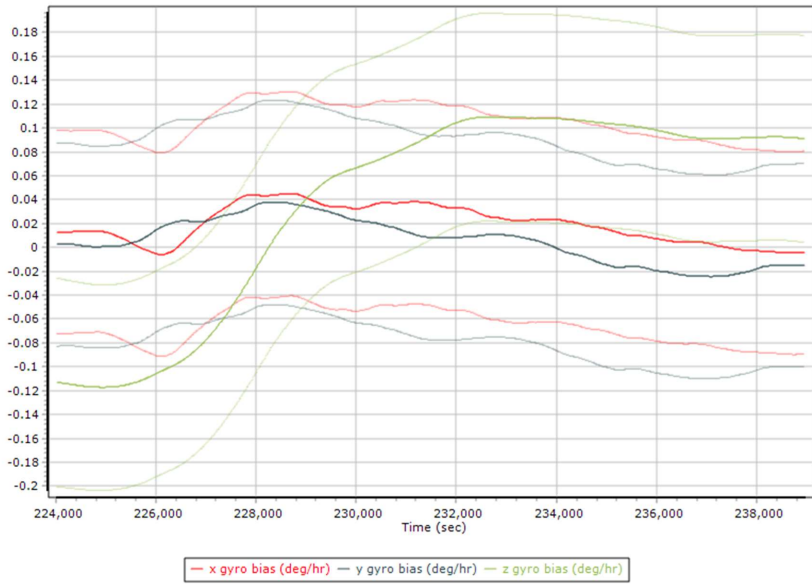
PDOP



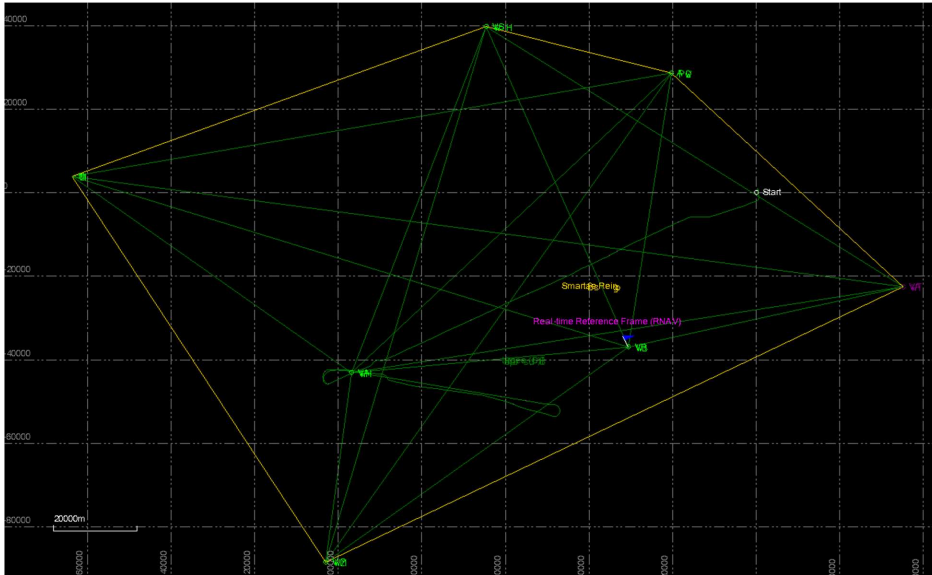
Processing Mode







PTG19092B



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

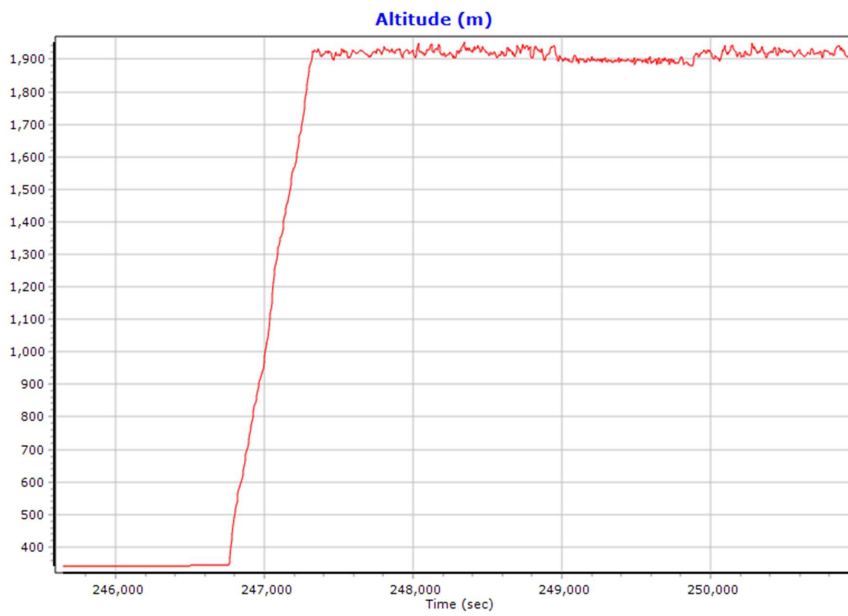
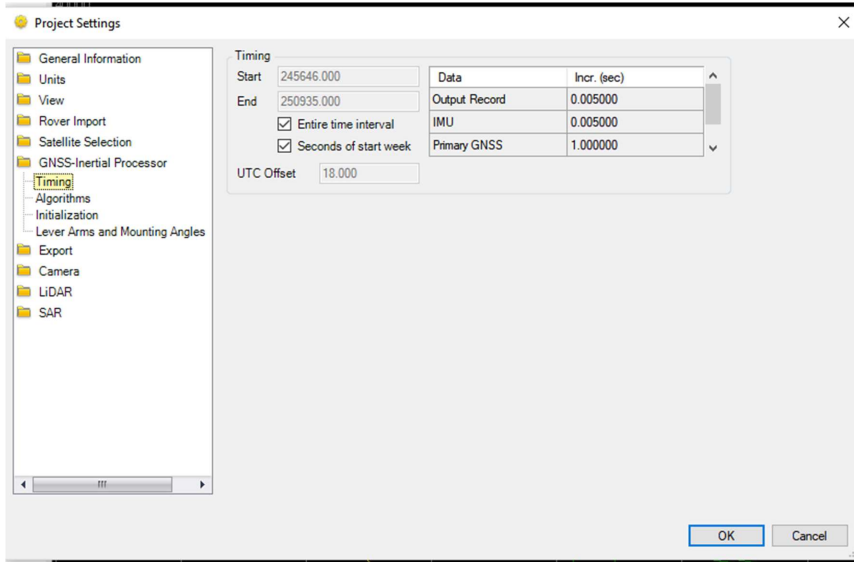
| Stabilized Mount to IMU Lever Arm | Stabilized Mount to IMU Mounting Angles |
|-----------------------------------|-----------------------------------------|
| X: -0.034 m | X: 0.000 deg |
| Y: -0.100 m | Y: 0.000 deg |
| Z: -0.352 m | Z: 0.000 deg |

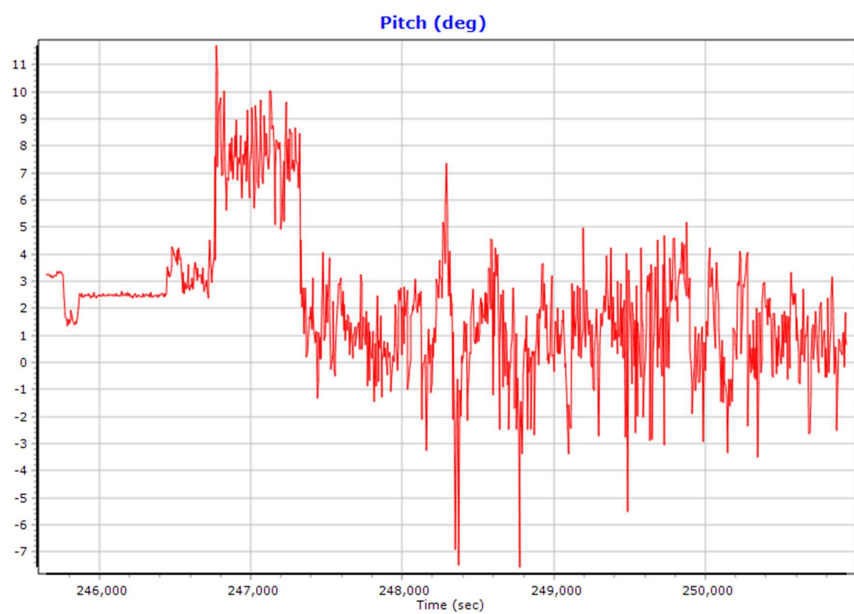
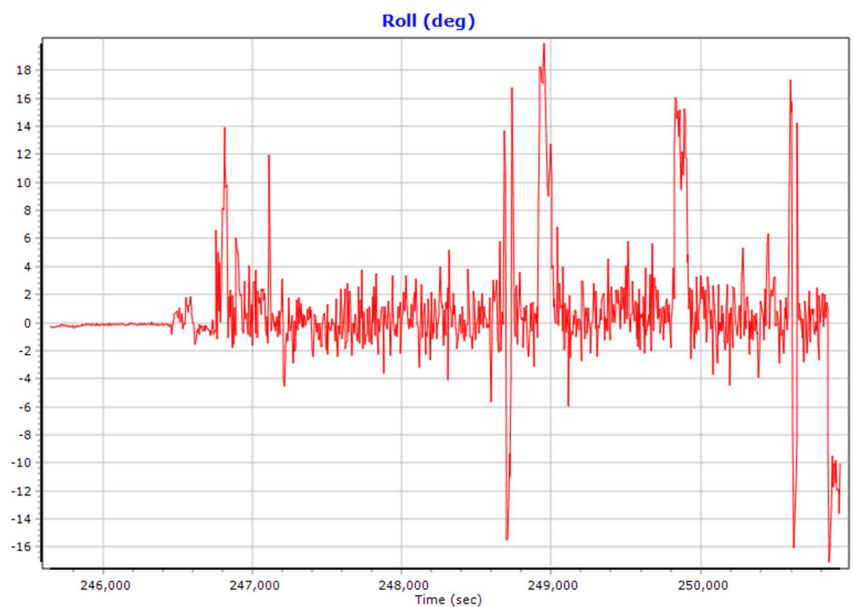
| Stabilized Mount to Primary GNSS Lever Arm | Aircraft to Stabilized Mount Mounting Angles |
|--------------------------------------------|----------------------------------------------|
| X: -0.054 m | X: 0.000 deg |
| Y: 0.140 m | Y: 0.000 deg |
| Z: -0.987 m | Z: 0.000 deg |

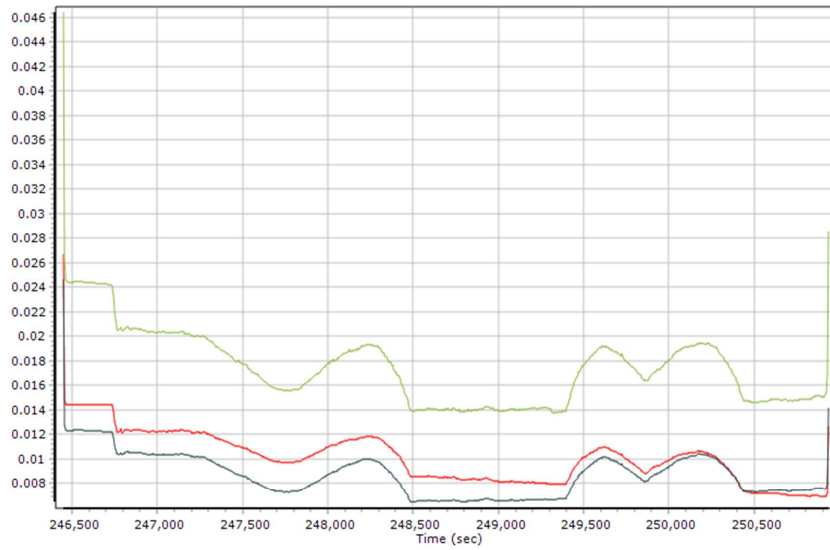
Standard Deviation: <3cm 10cm 50cm 1m 10m

Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

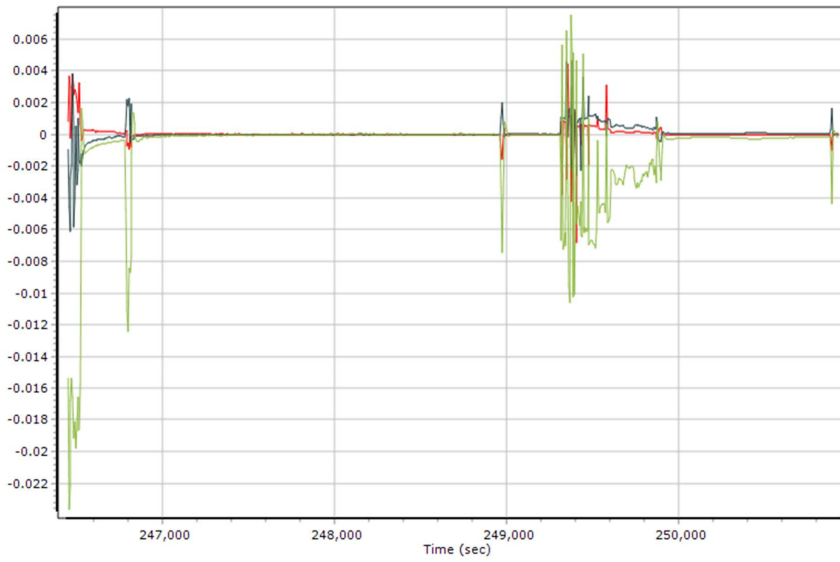
OK Cancel



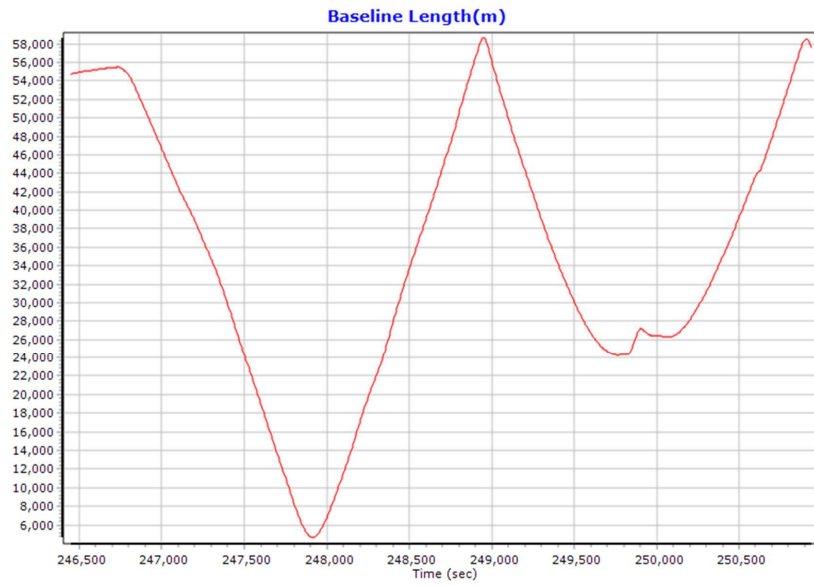
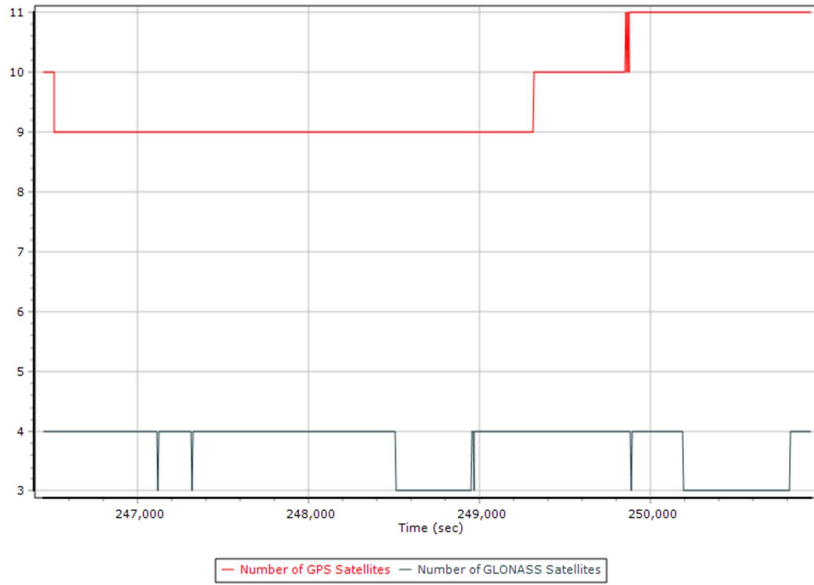


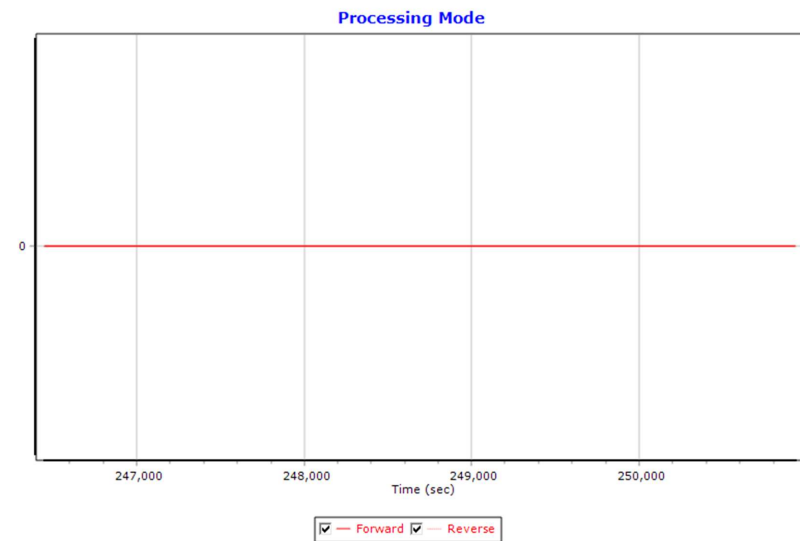
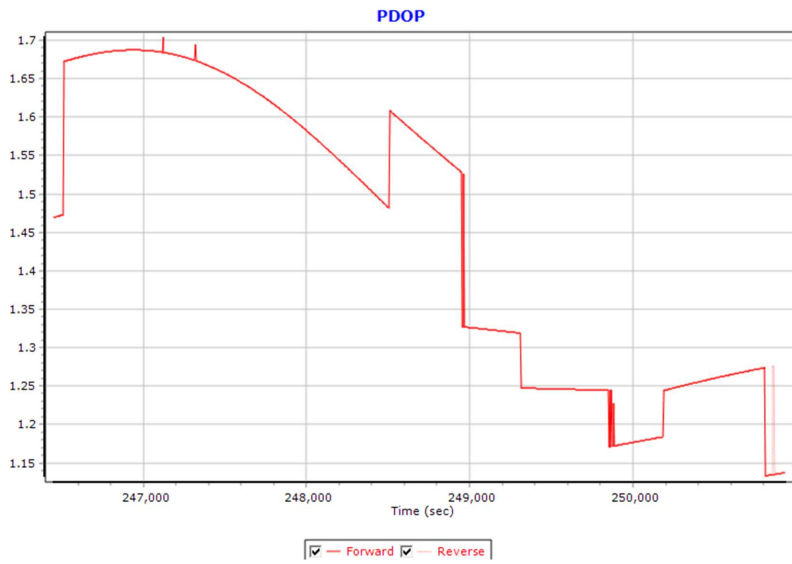


— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)

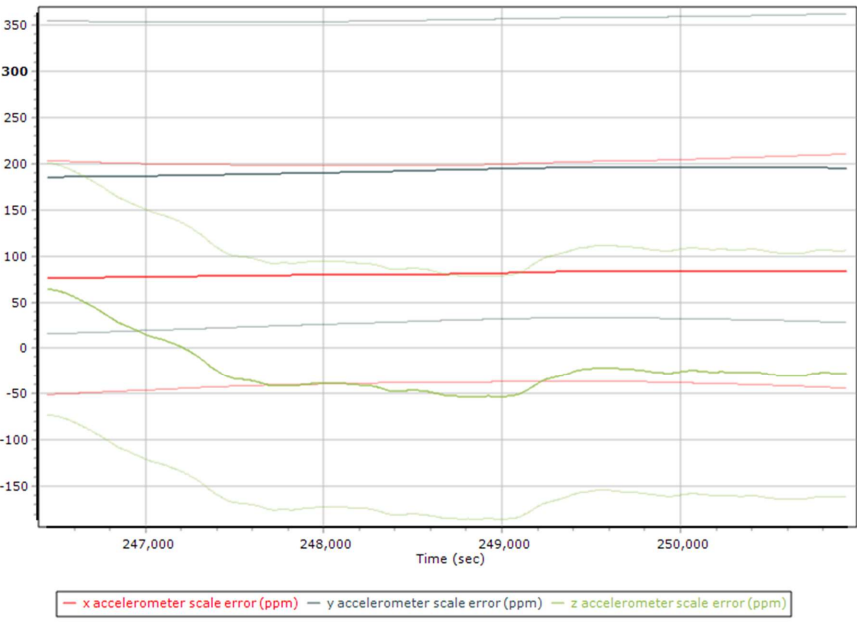
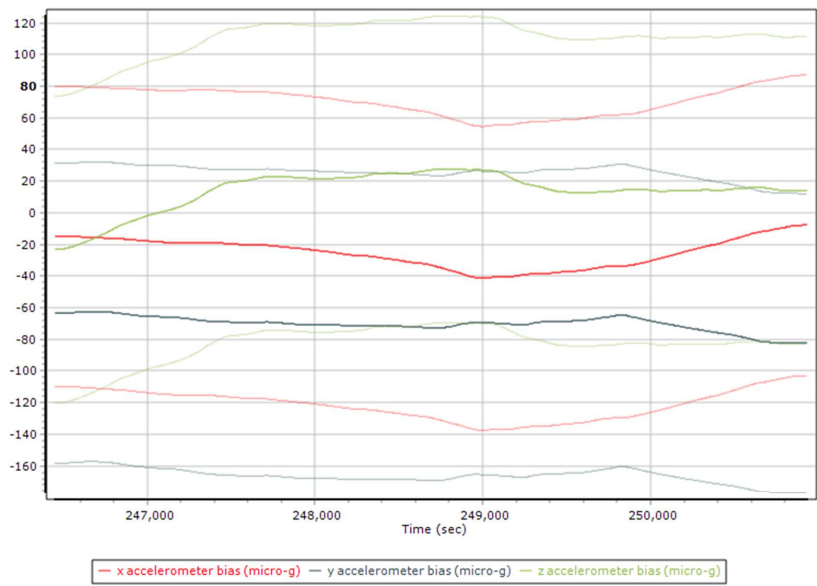


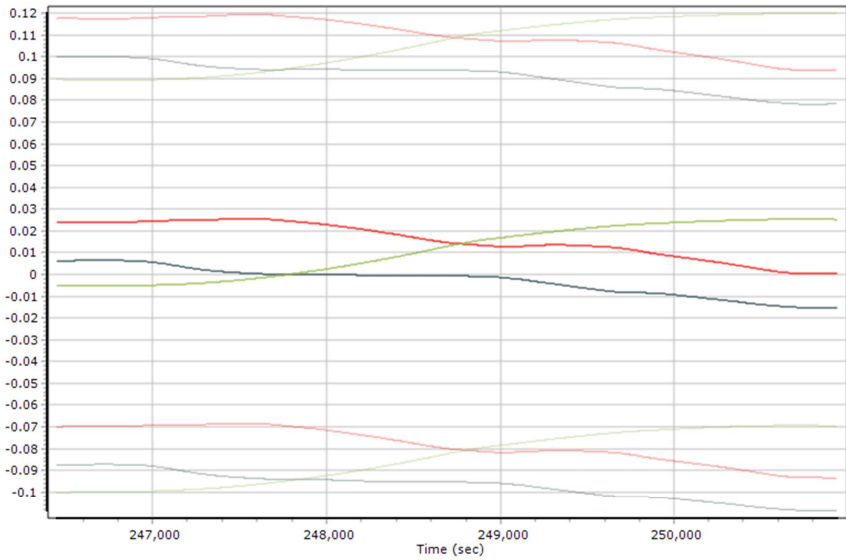
— North (m) — East (m) — Down (m) — DR mode



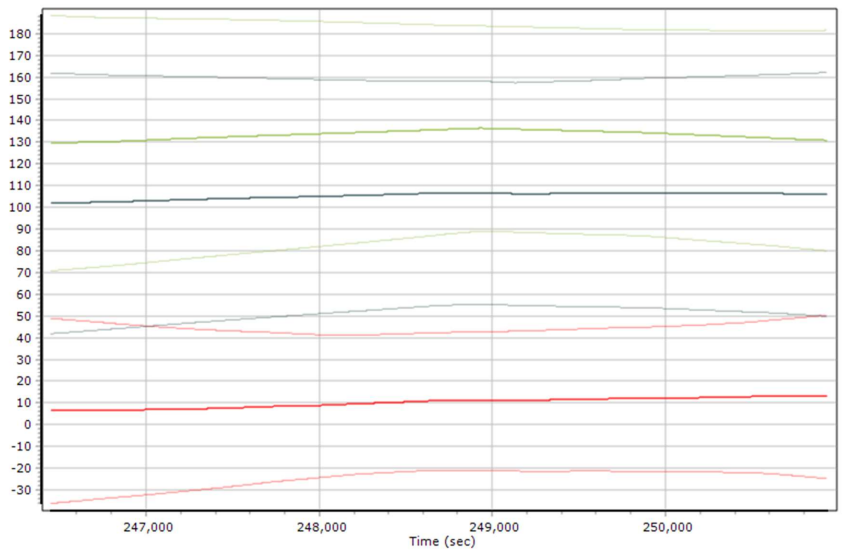


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



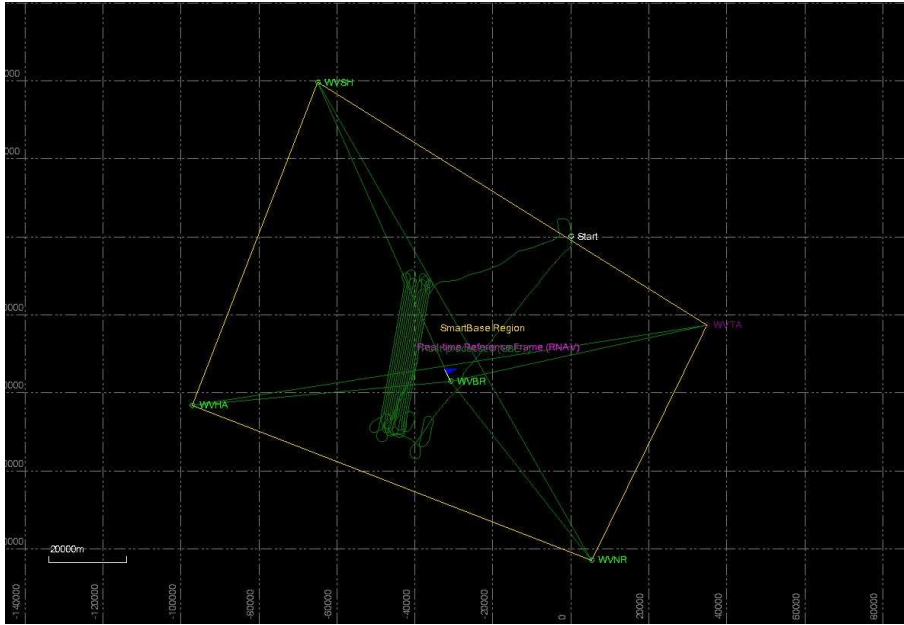


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



— x gyro scale error (ppm) — y gyro scale error (ppm) — z gyro scale error (ppm)

UNB19086A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
 - Export
 - Camera
 - LiDAR

| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
|----------------------------|----------------------------------|
| X: 0.034 m | X: 0.000 deg |
| Y: 0.018 m | Y: 0.000 deg |
| Z: -0.155 m | Z: 0.000 deg |

| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
|-------------------------------------|---------------------------------------|
| X: -0.118 m | X: 0.000 deg |
| Y: -0.062 m | Y: 0.000 deg |
| Z: -0.952 m | Z: 0.000 deg |

Standard Deviation

Project Settings

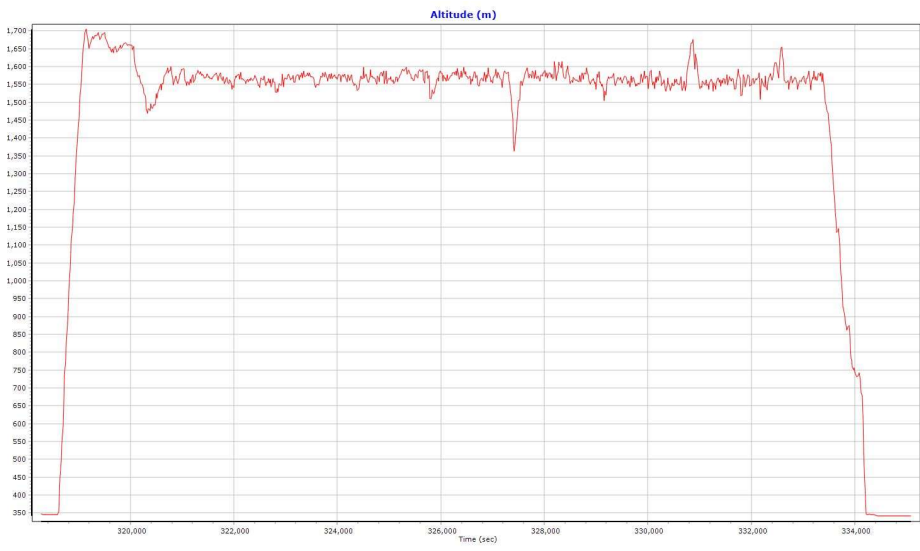
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles

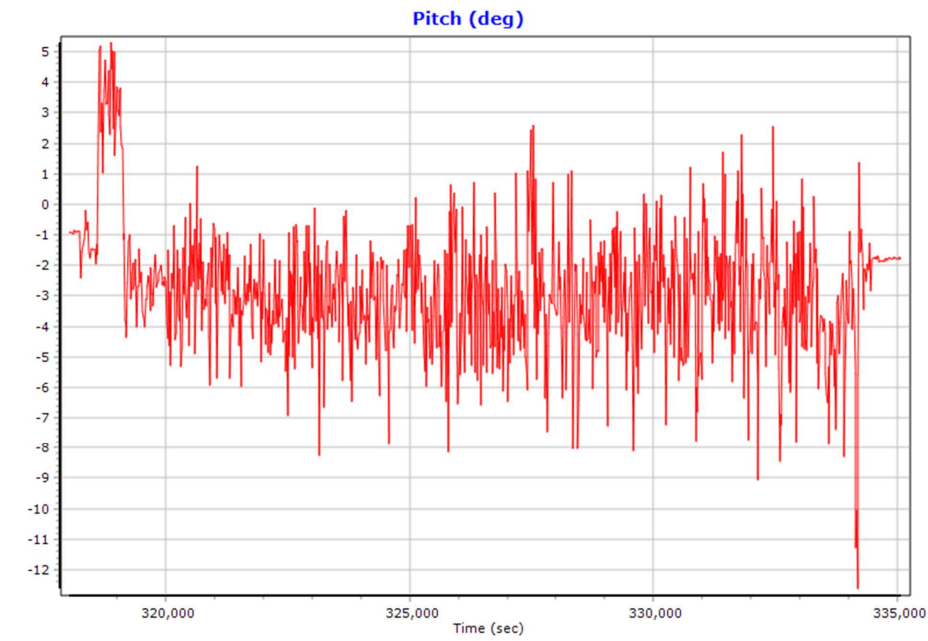
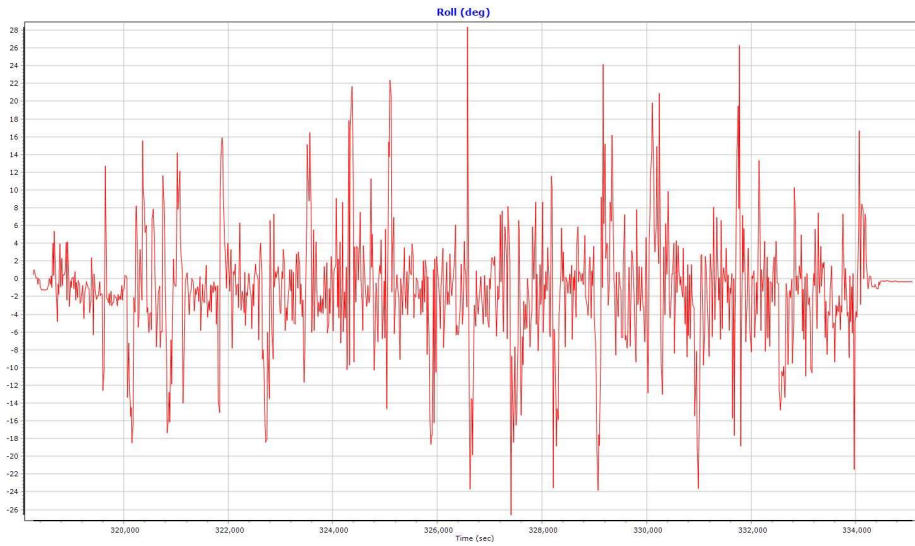
Timing

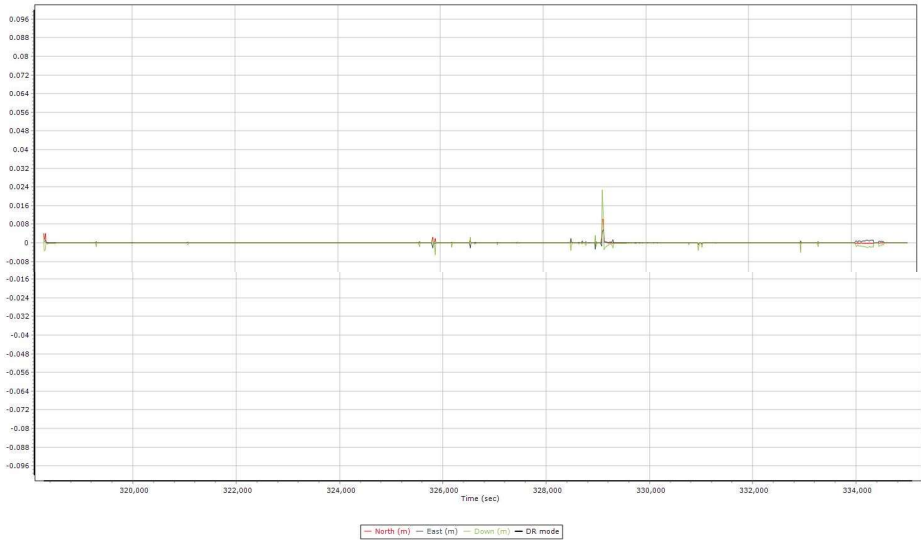
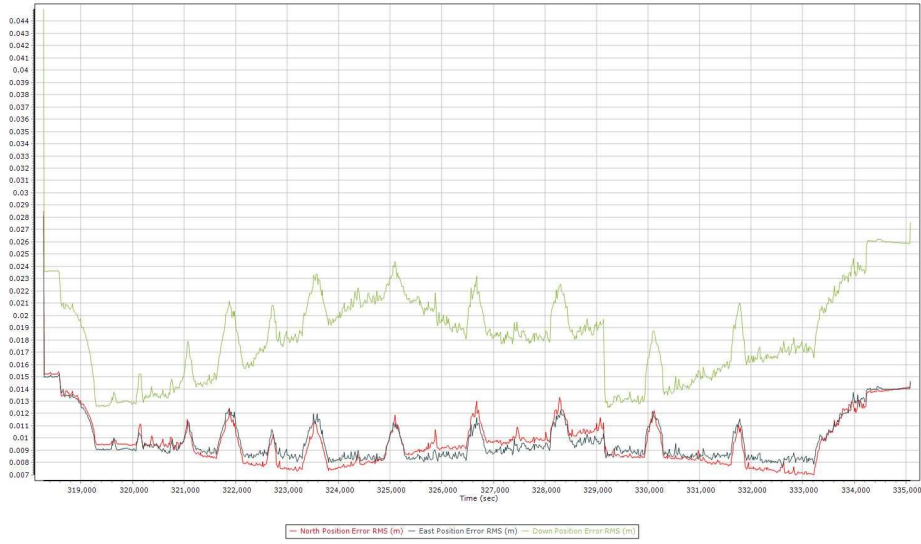
Start: 318011.000
End: 335094.000
UTC Offset: 18.000

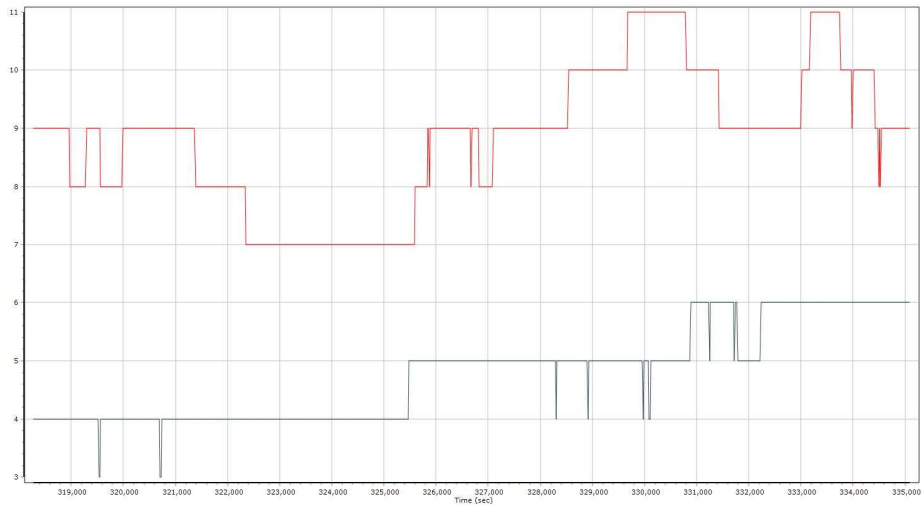
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

Entire time interval
 Seconds of start week

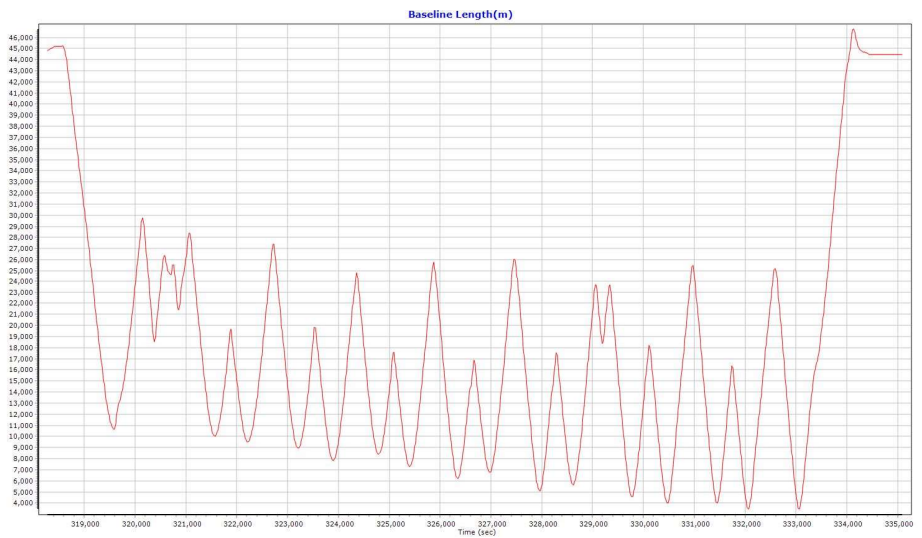


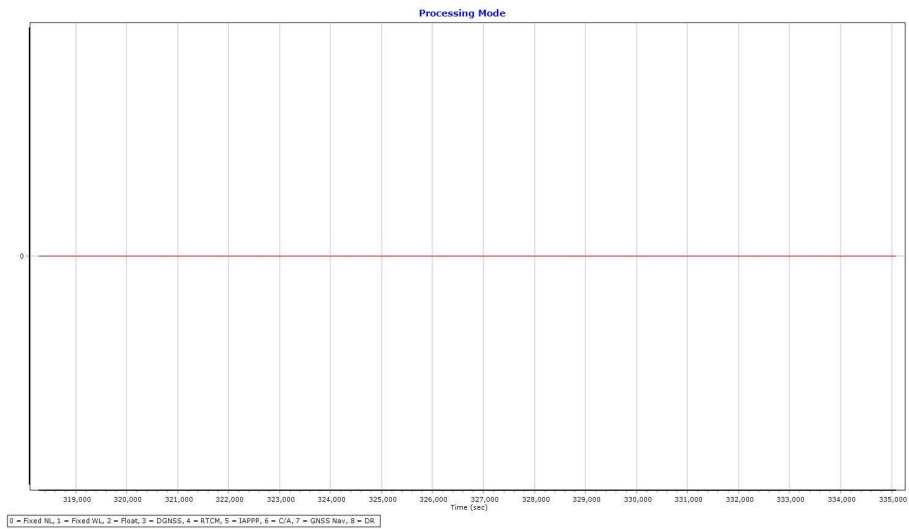
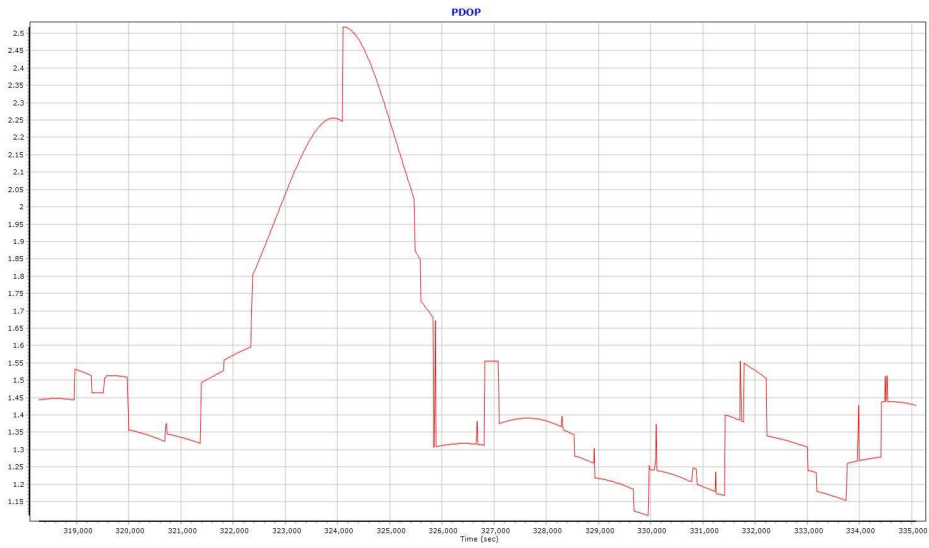


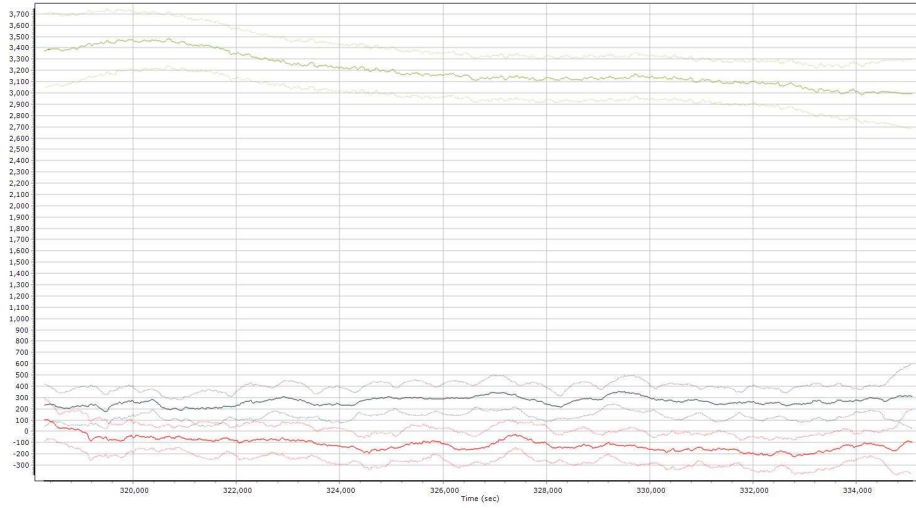




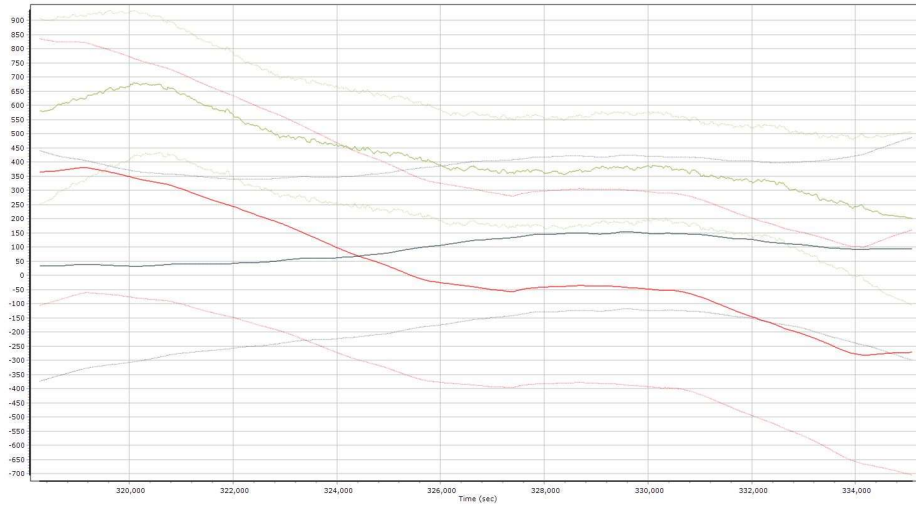
— Number of GPS Satellites — Number of GLONASS Satellites



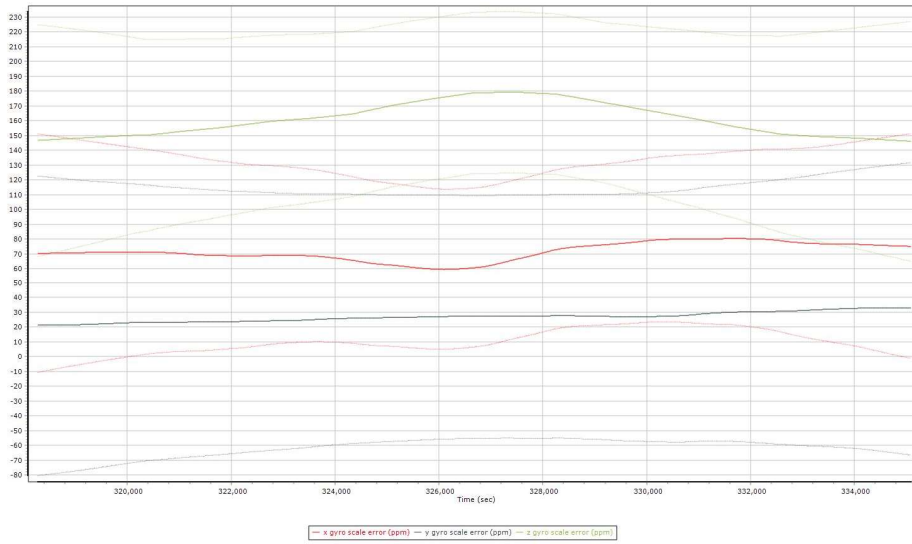
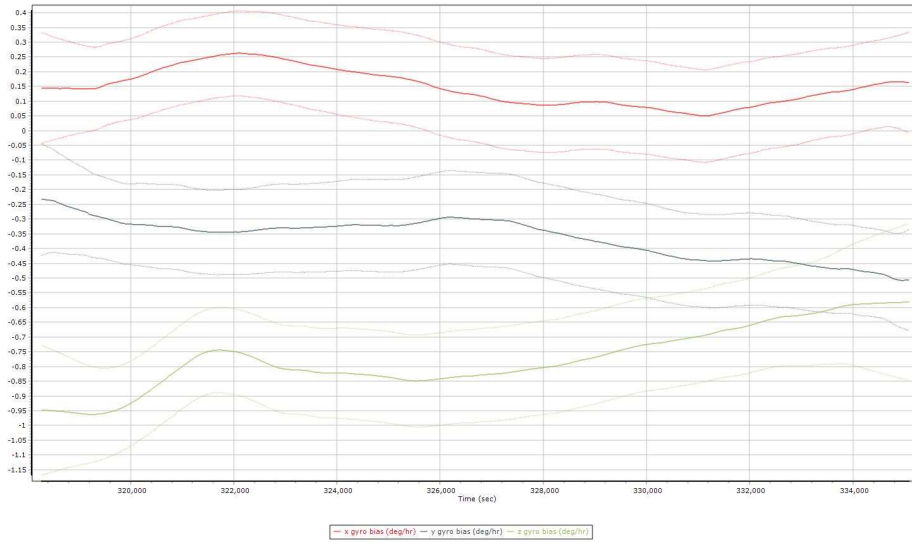




— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



Project Settings

- General Information
- Units
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- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
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 - Algorithms
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 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

Reference to IMU Lever Arm

X: 0.034 m

Y: 0.018 m

Z: -0.155 m

Reference to IMU Mounting Angles

X: 0.000 deg

Y: 0.000 deg

Z: 0.000 deg

Reference to Primary GNSS Lever Arm

X: -0.118 m

Y: -0.062 m

Z: -0.952 m

Standard Deviation: <3cm 10cm 50cm 1m 10m

Aircraft to Reference Mounting Angles

X: 0.000 deg

Y: 0.000 deg

Z: 0.000 deg

OK Cancel

Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

Timing

Start: 392788.789 Data Incr. (sec)

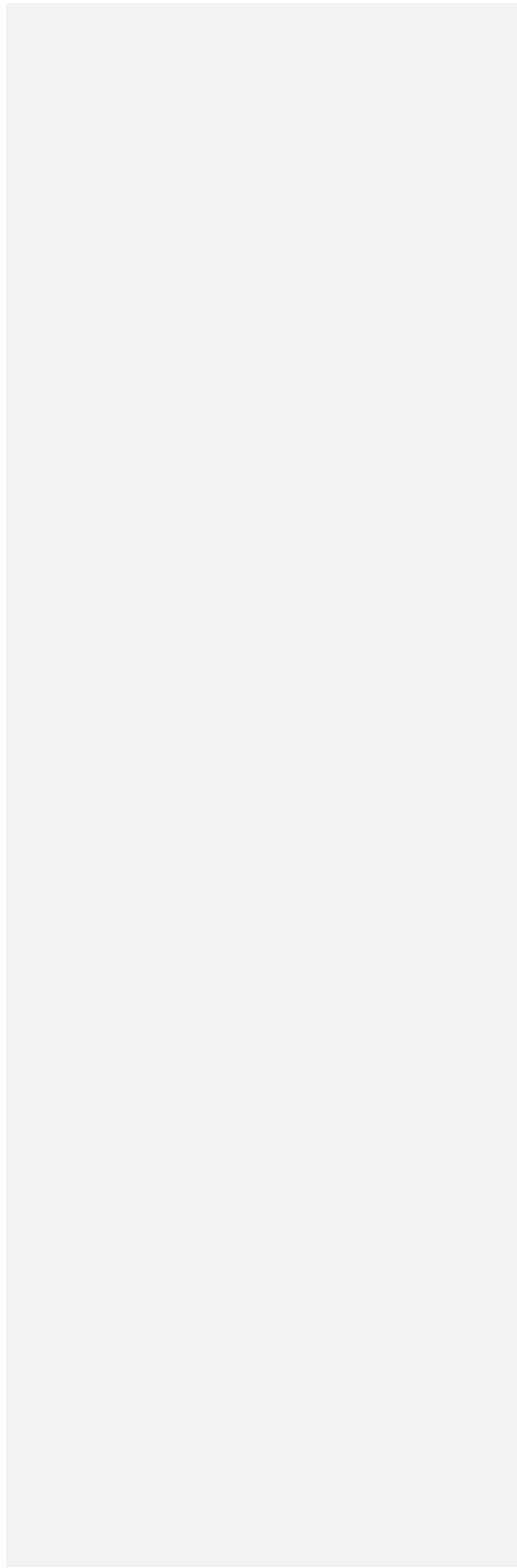
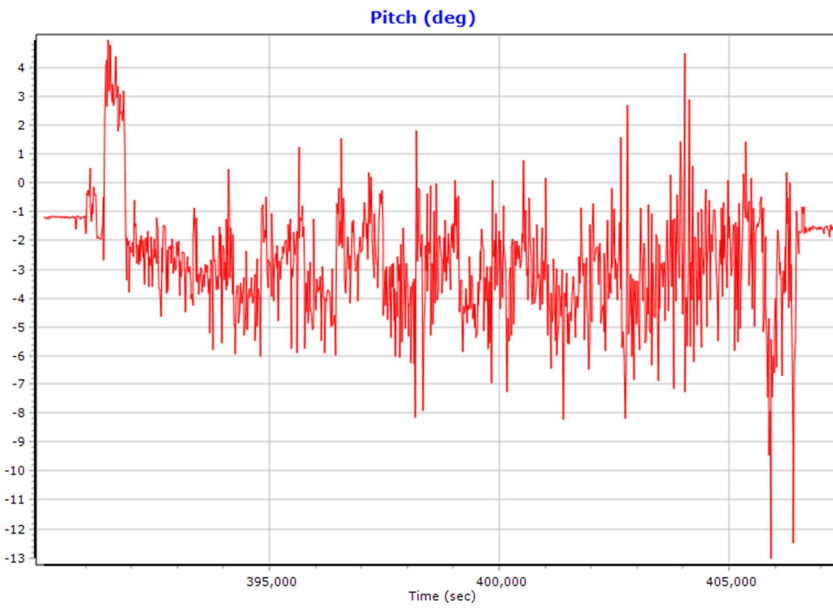
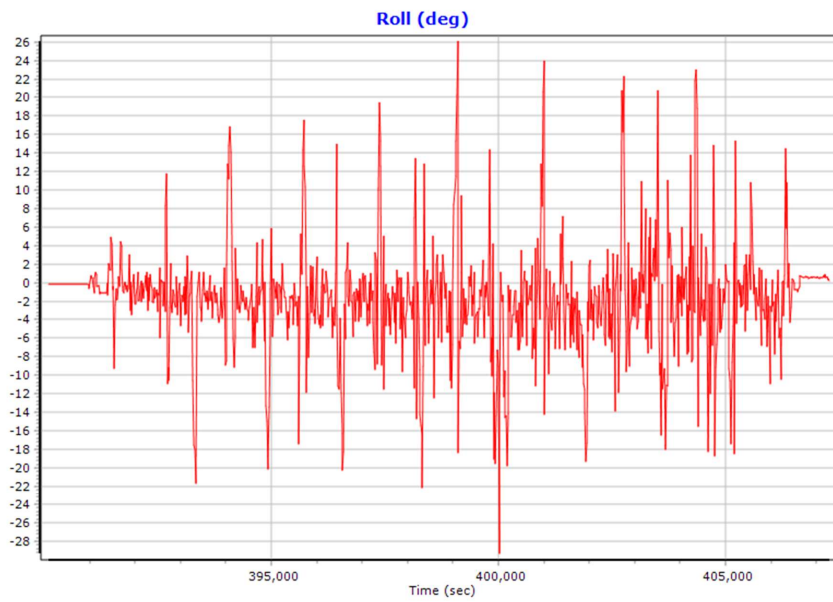
End: 405064.463 Output Record 0.005000

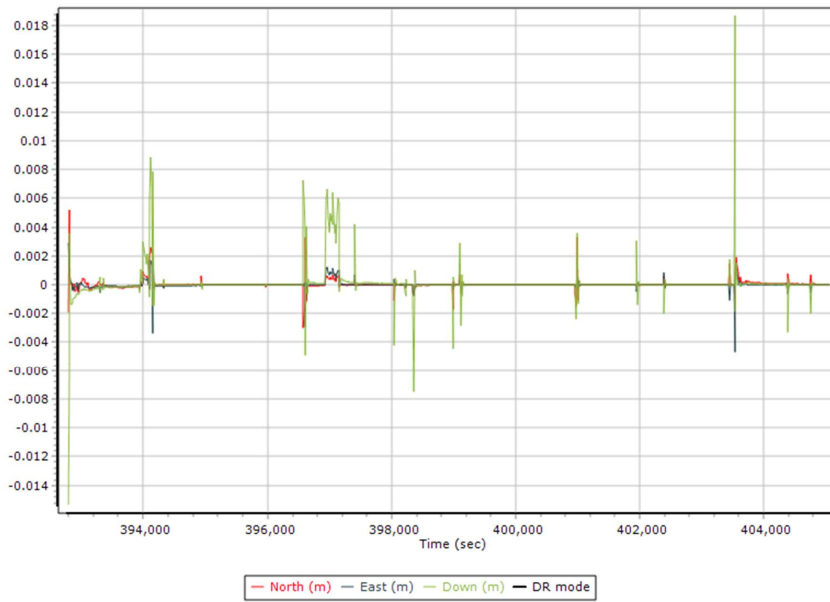
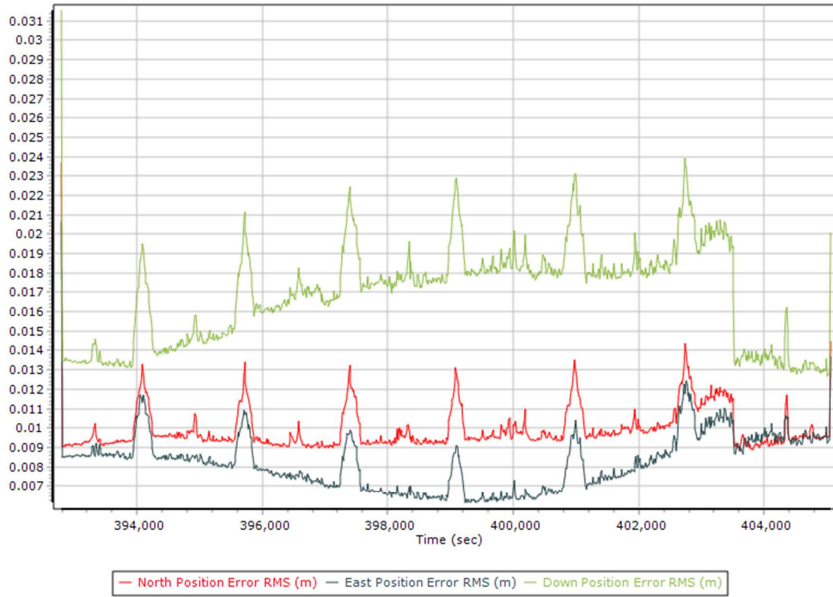
Entire time interval IMU 0.005000

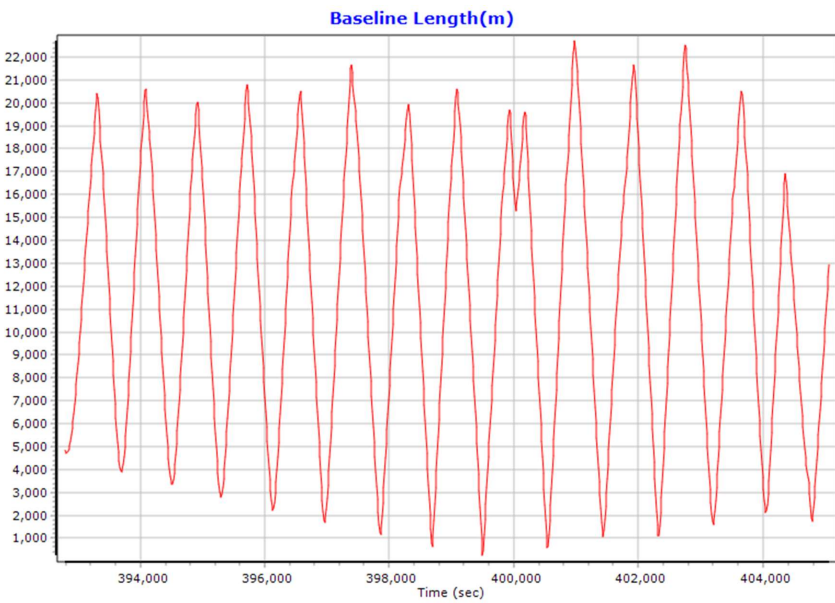
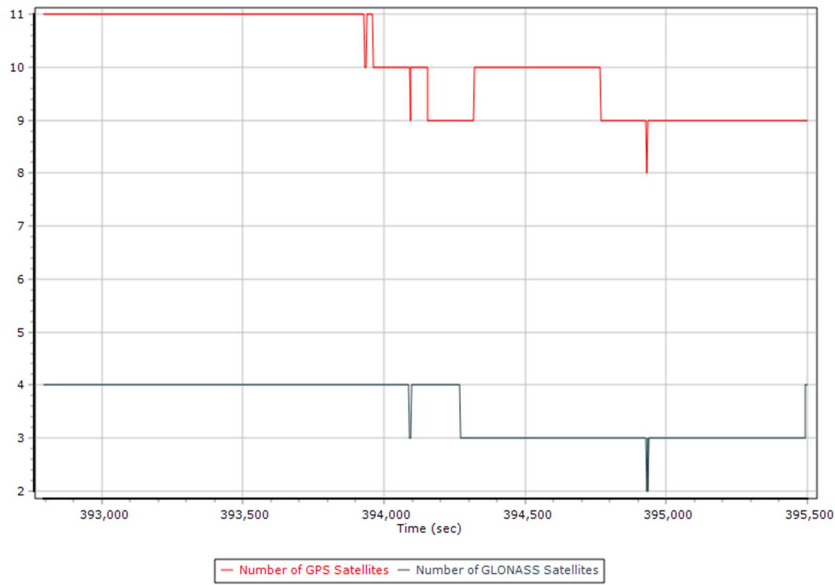
Seconds of start week Primary GNSS 1.000000

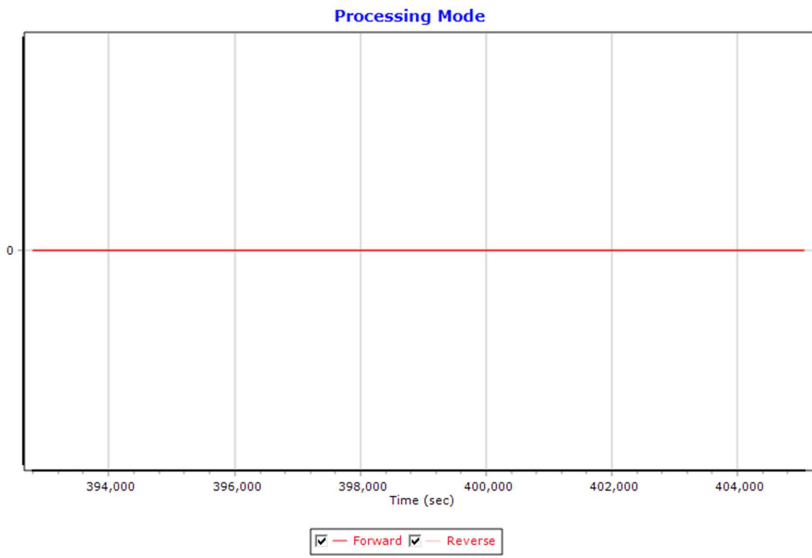
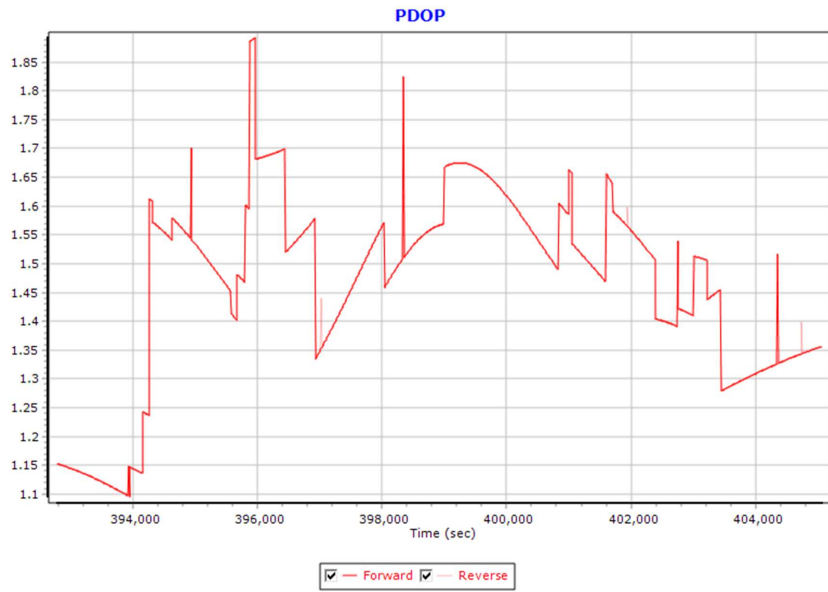
UTC Offset: 18.000

OK Cancel

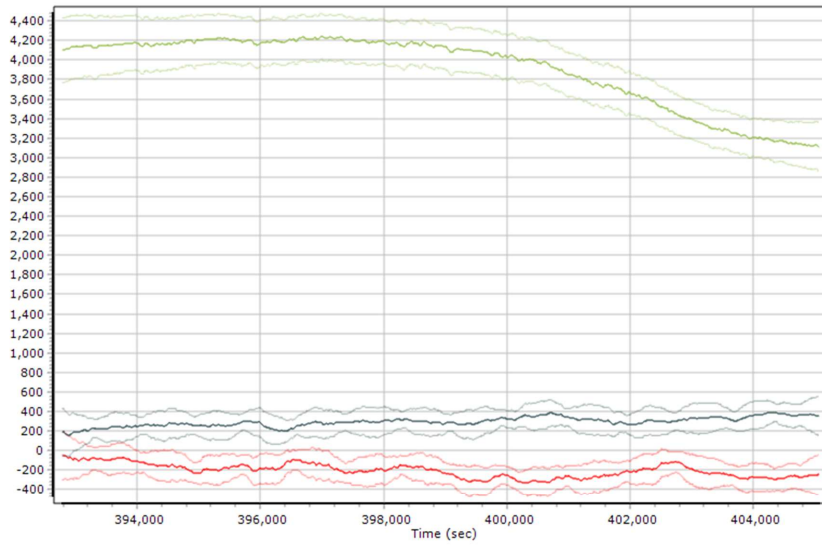




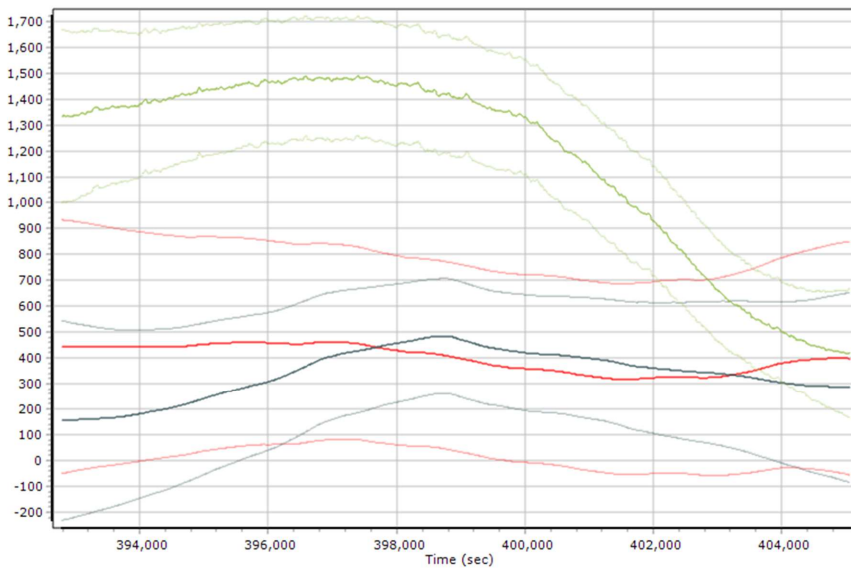




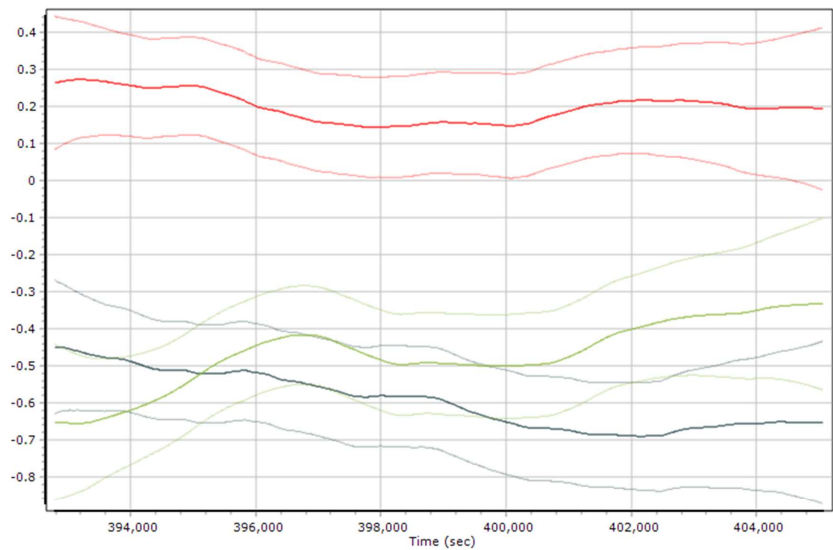
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



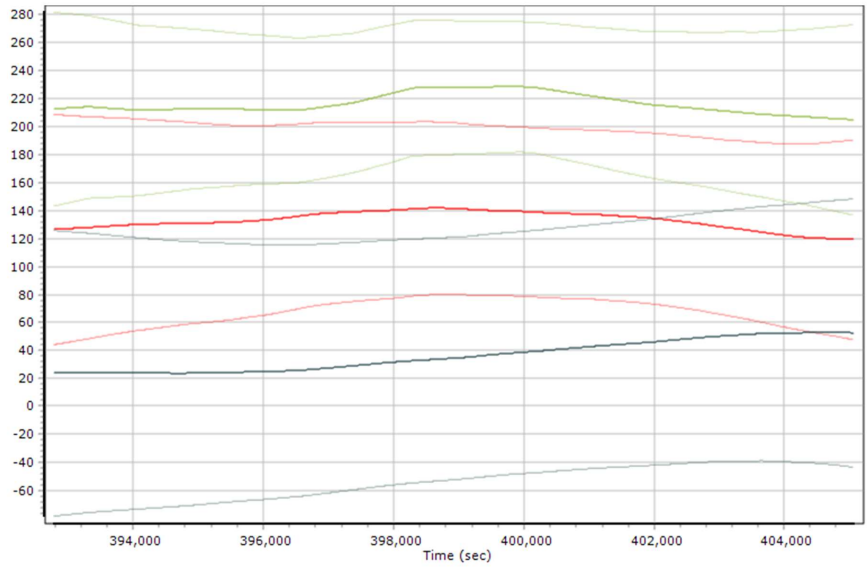
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

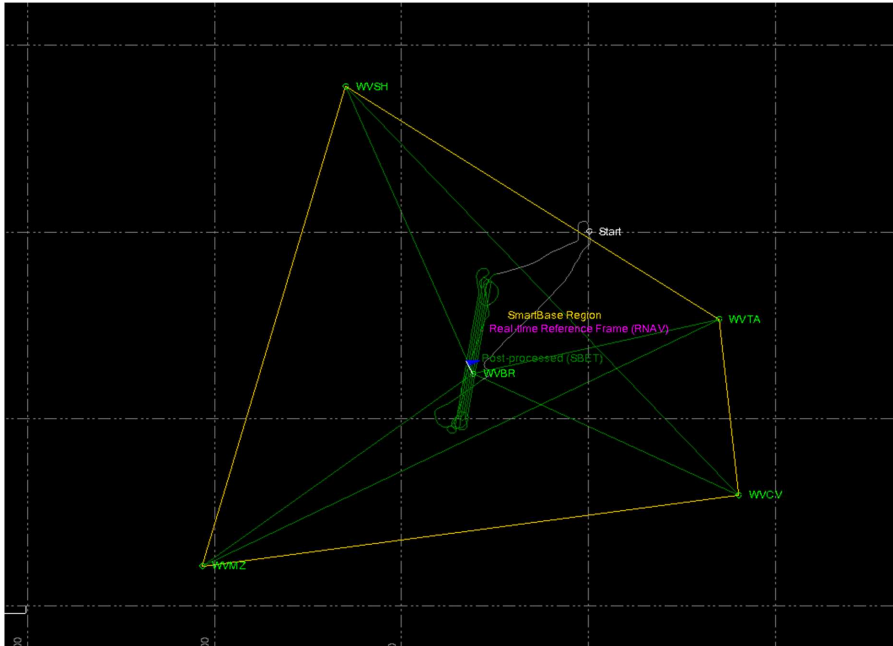


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



— x gyro scale error (ppm) — y gyro scale error (ppm) — z gyro scale error (ppm)

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Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LIDAR
- SAR

| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
|----------------------------|----------------------------------|
| X: 0.034 m | X: 0.000 deg |
| Y: 0.018 m | Y: 0.000 deg |
| Z: -0.155 m | Z: 0.000 deg |

| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
|-------------------------------------|---------------------------------------|
| X: -0.118 m | X: 0.000 deg |
| Y: -0.062 m | Y: 0.000 deg |
| Z: -0.952 m | Z: 0.000 deg |

Standard Deviation:

<3cm 10cm 50cm 1m 10m

Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
- Timing**
- Algorithms

Timing

Start: 418128.002

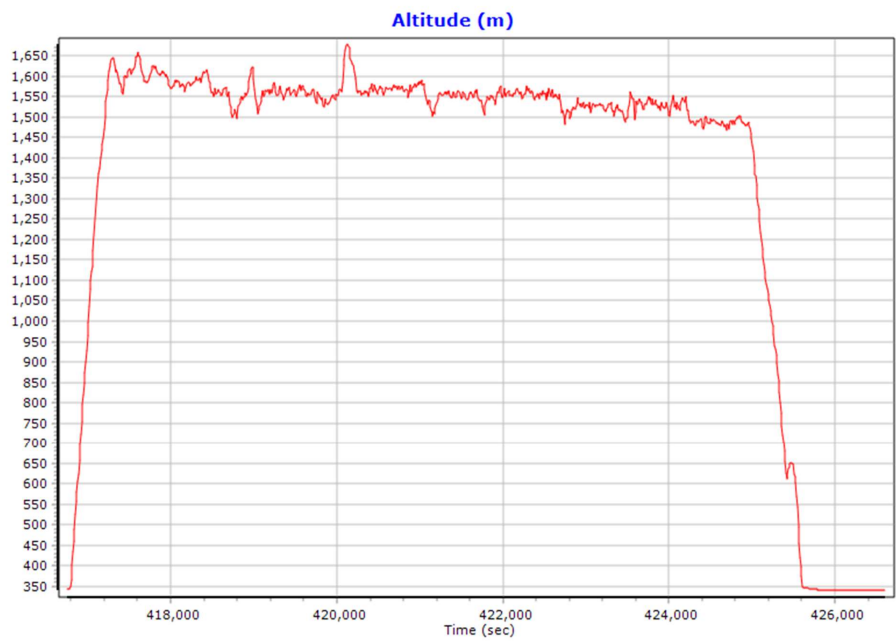
End: 425000.238

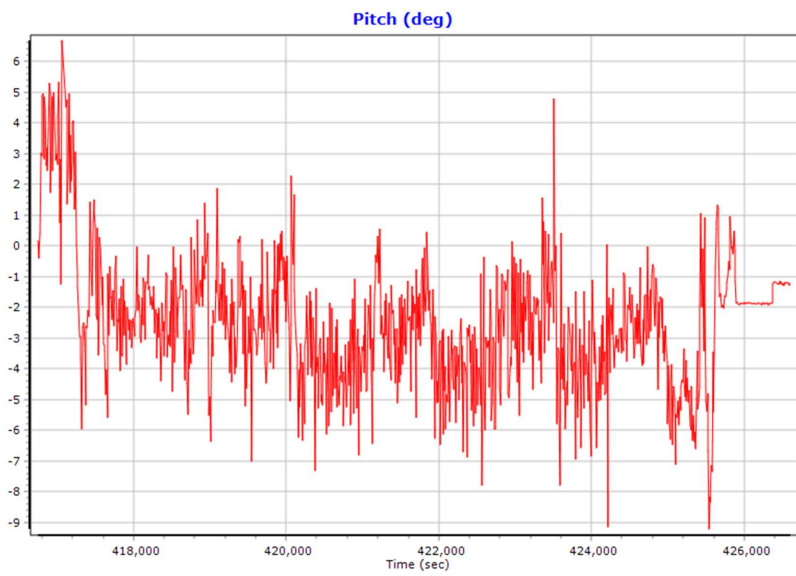
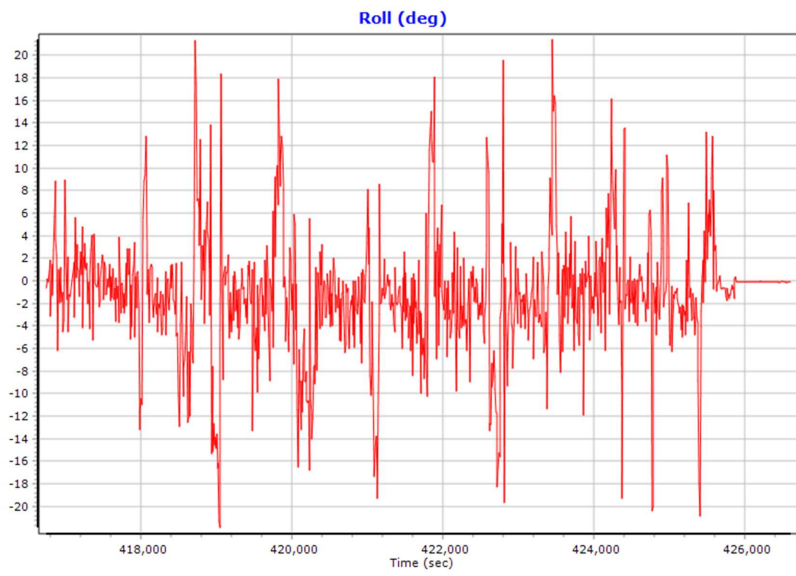
Entire time interval

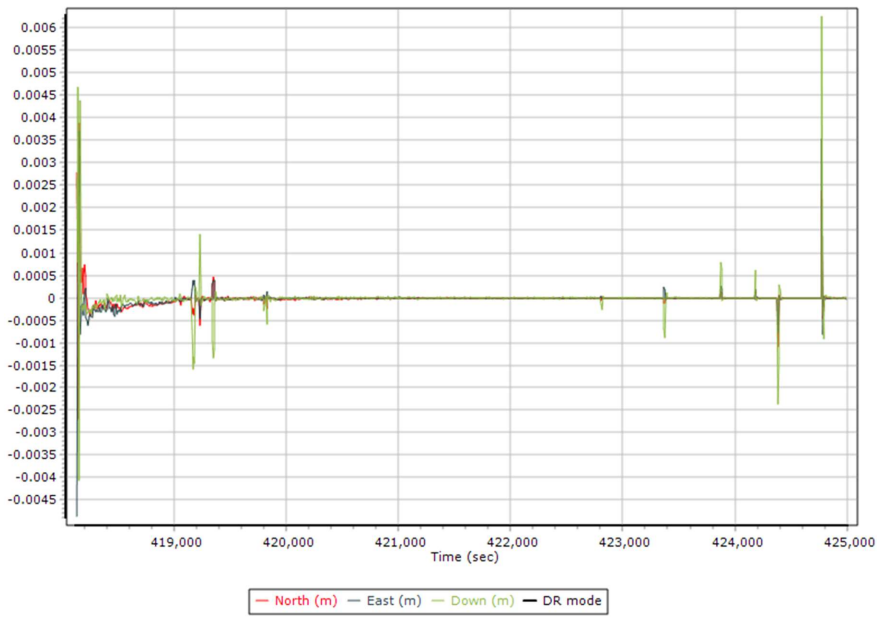
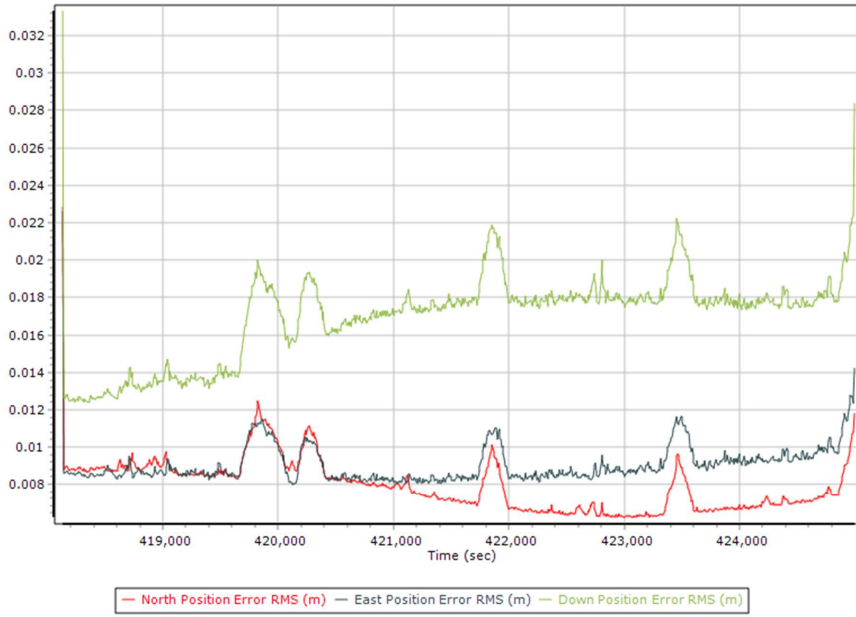
Seconds of start week

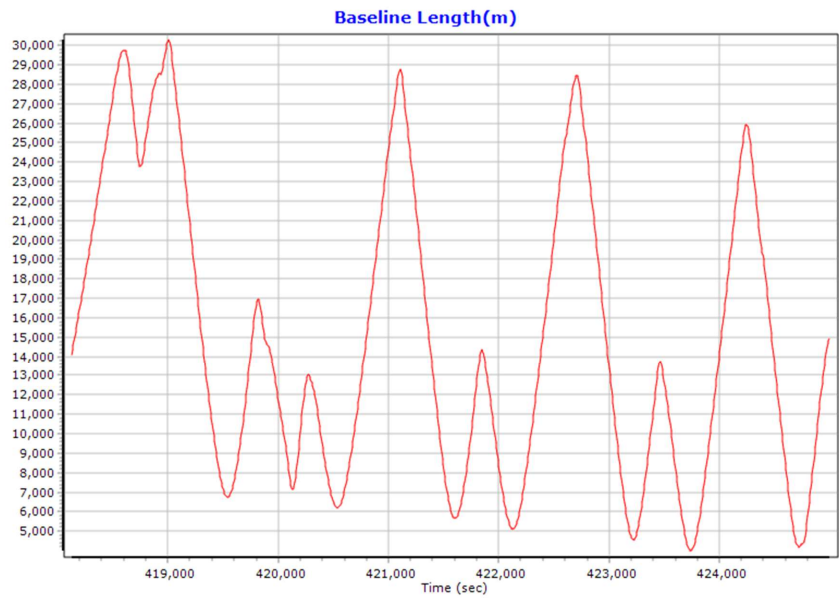
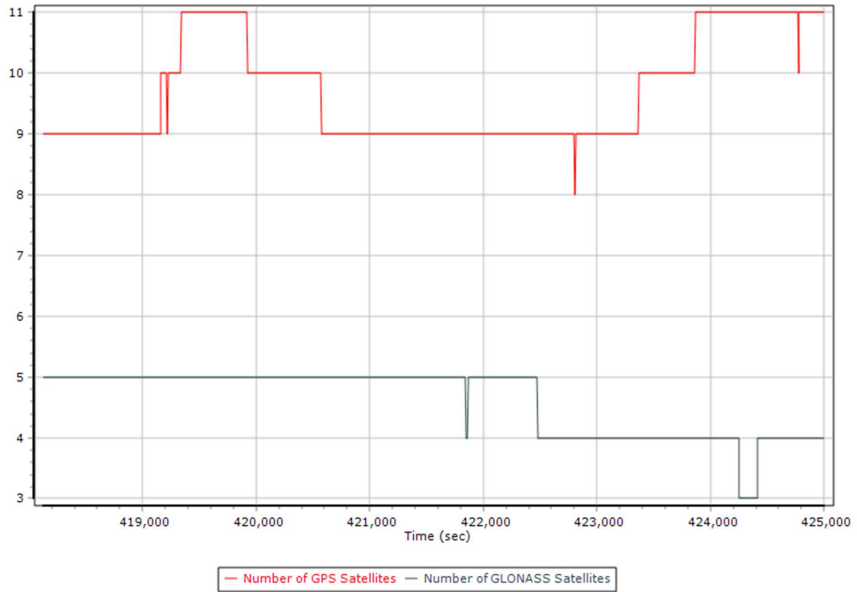
UTC Offset: 18.000

| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

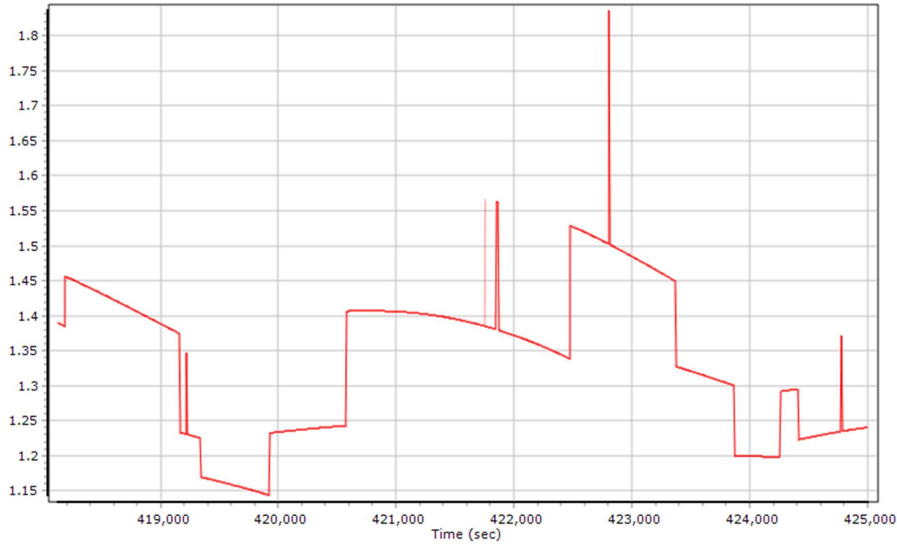






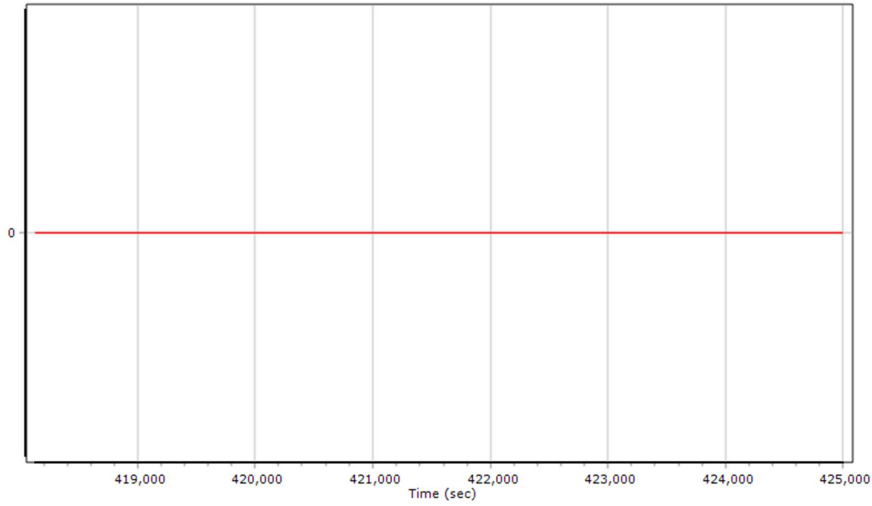


PDOP



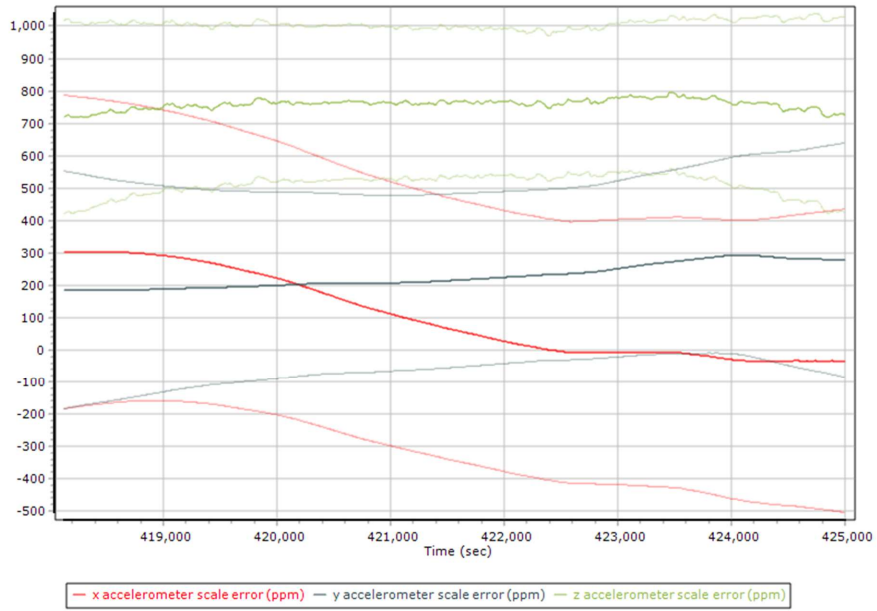
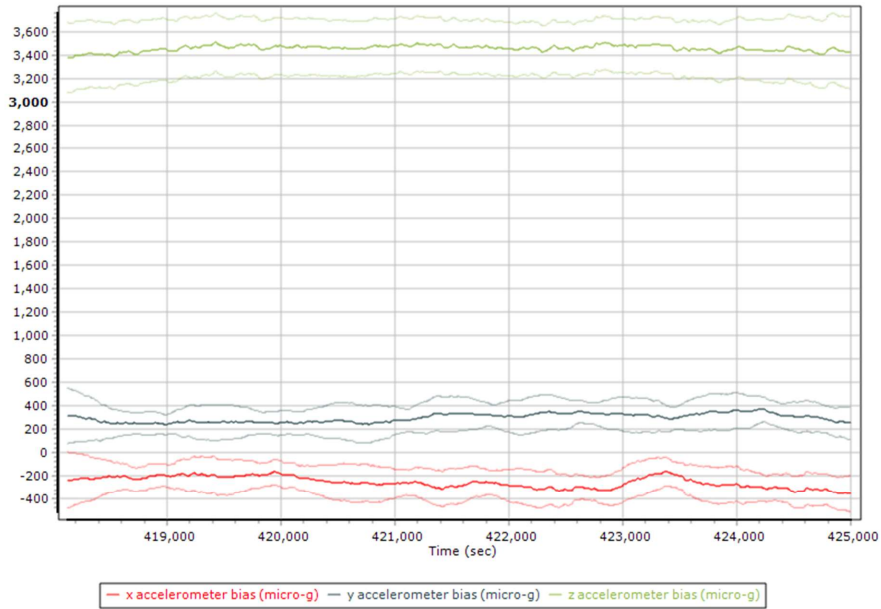
Forward Reverse

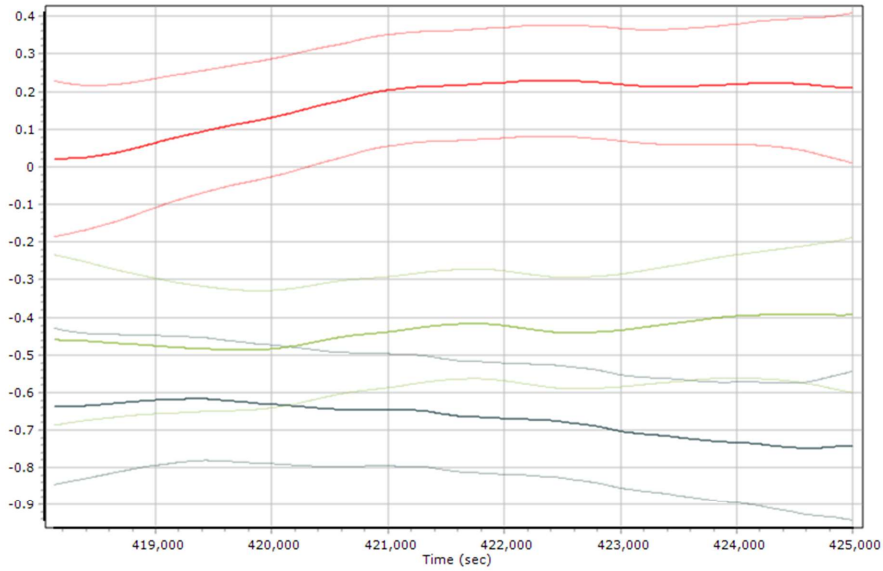
Processing Mode



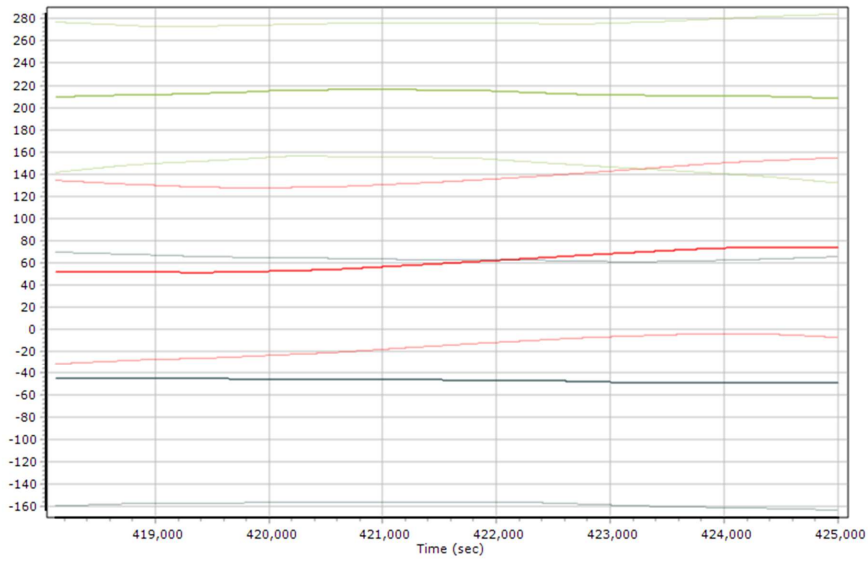
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



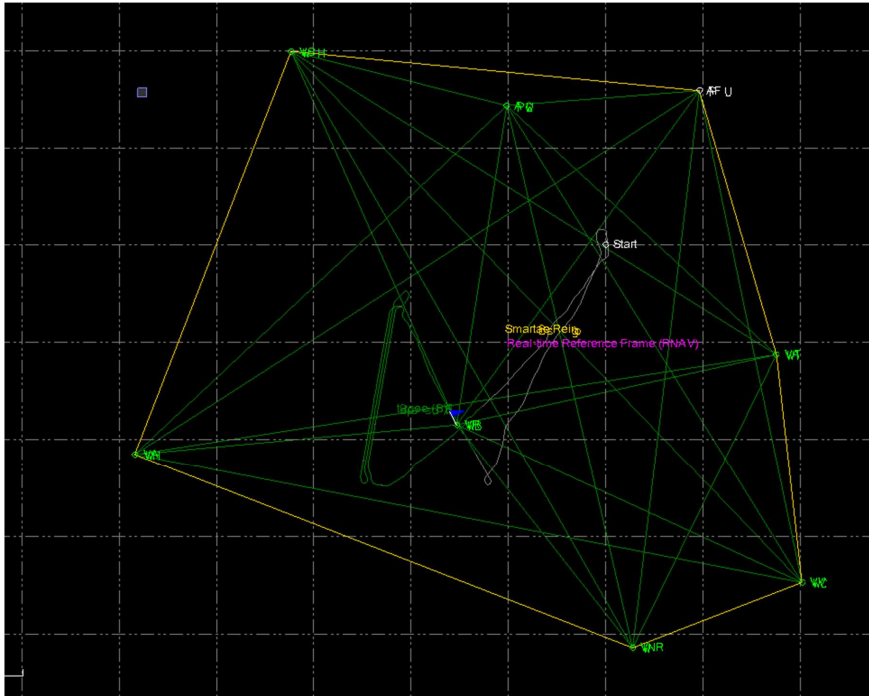


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



— x gyro scale error (ppm) — y gyro scale error (ppm) — z gyro scale error (ppm)

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| | | | |
|-------------------------------------|---------------------------------------|---------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.118 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.062 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.952 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | <input type="range" value="3cm"/> | | |
| | <3cm 10cm 50cm 1m 10m | | |

Timing

Start

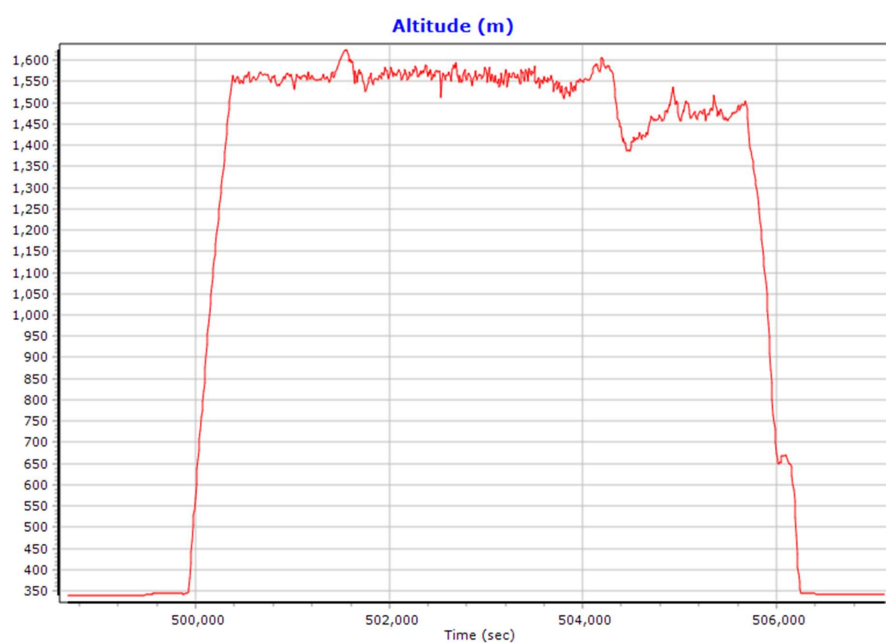
End

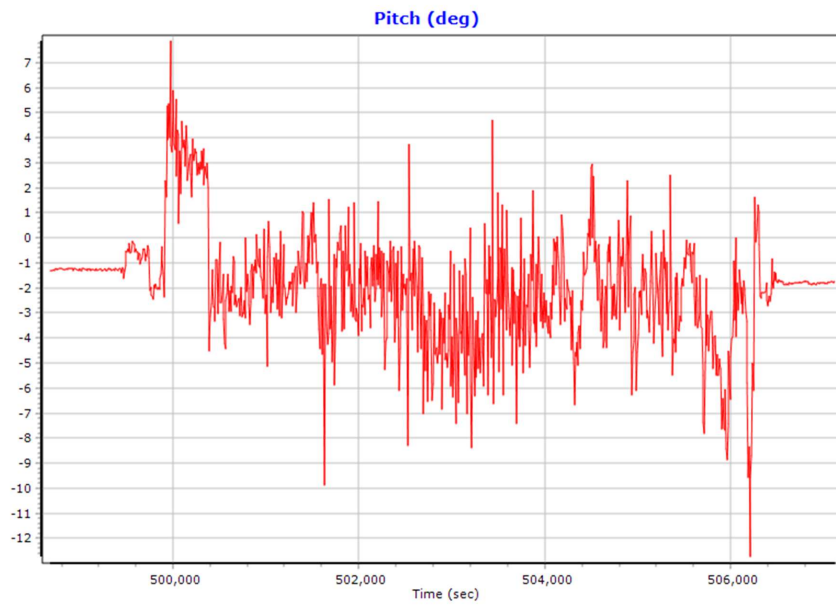
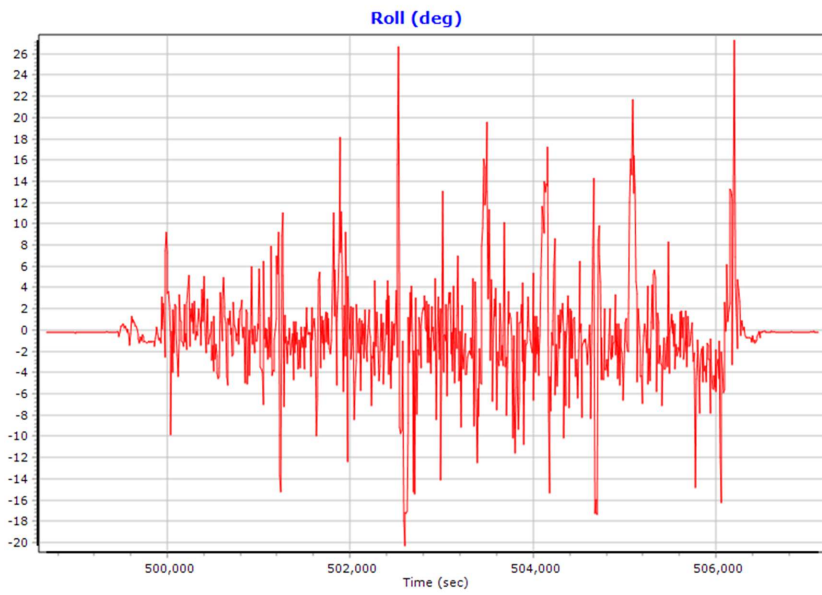
Entire time interval

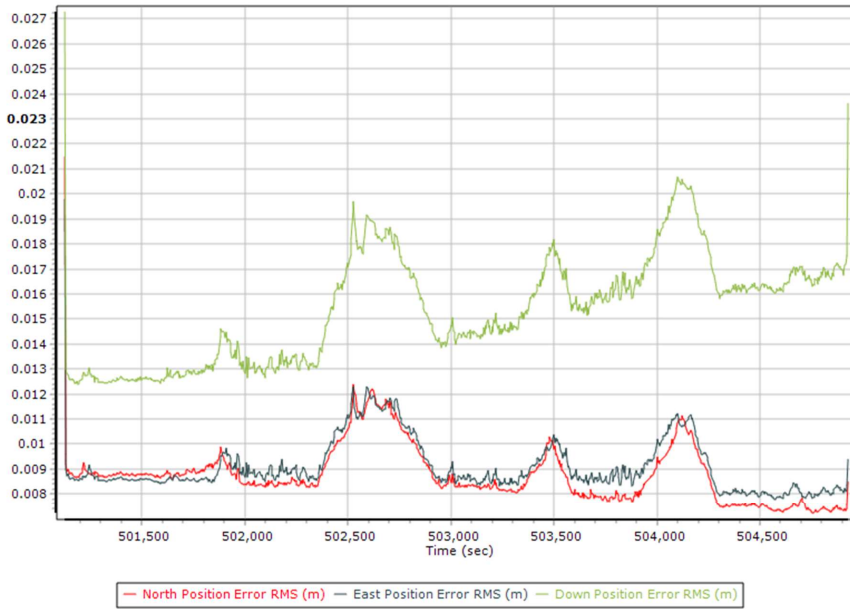
Seconds of start week

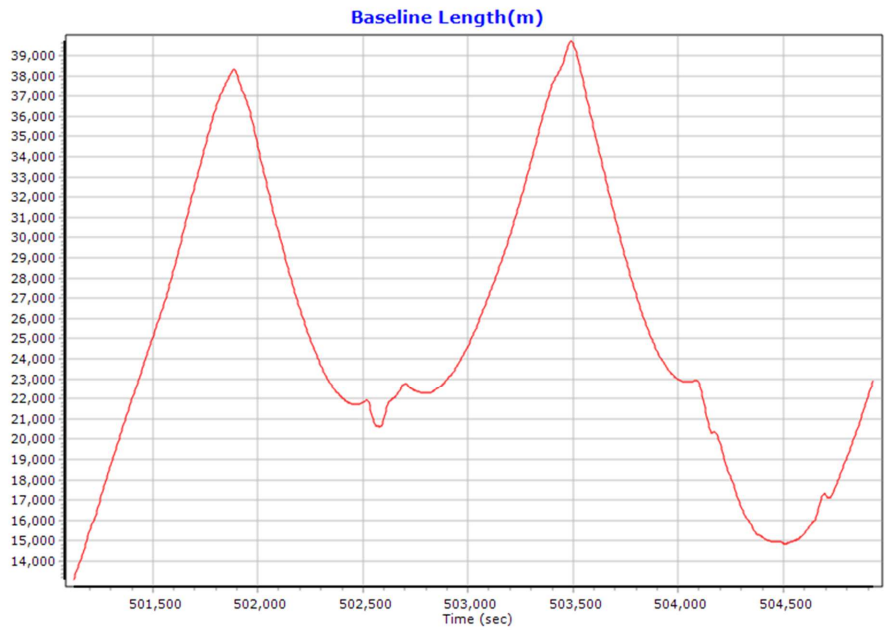
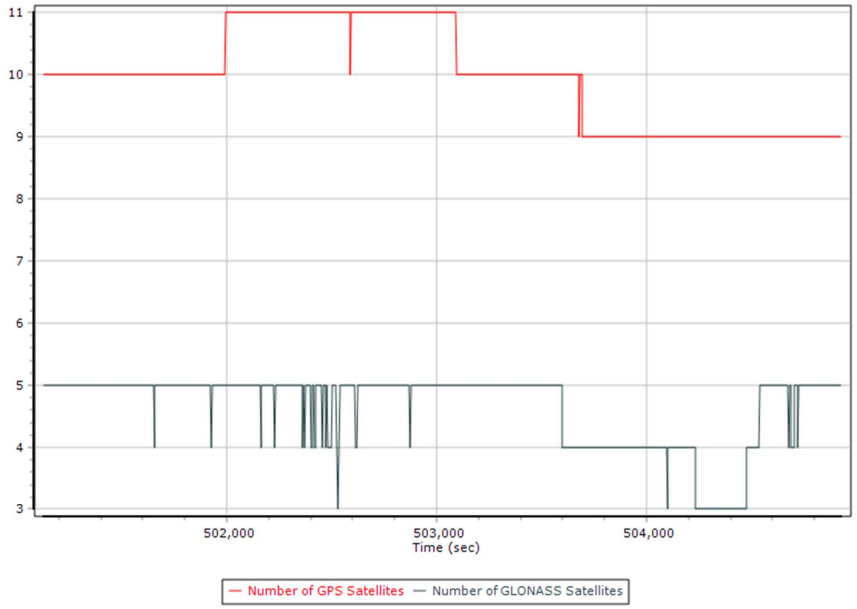
UTC Offset

| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

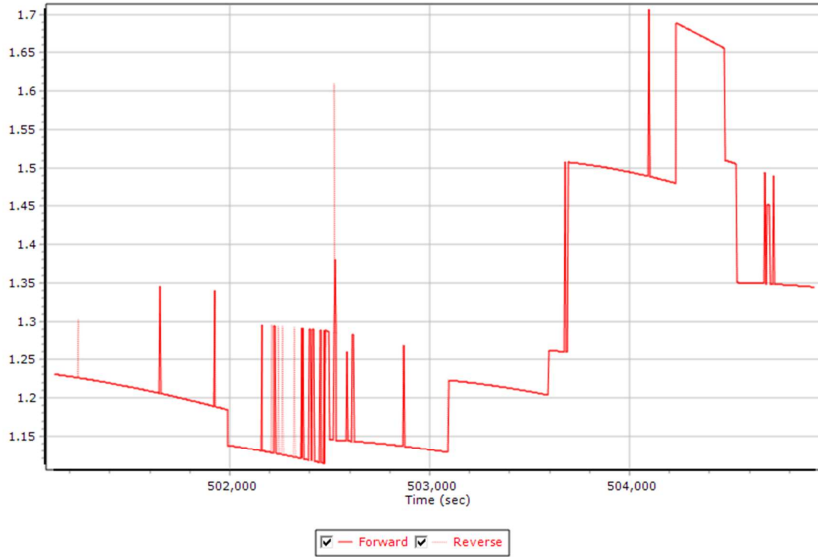








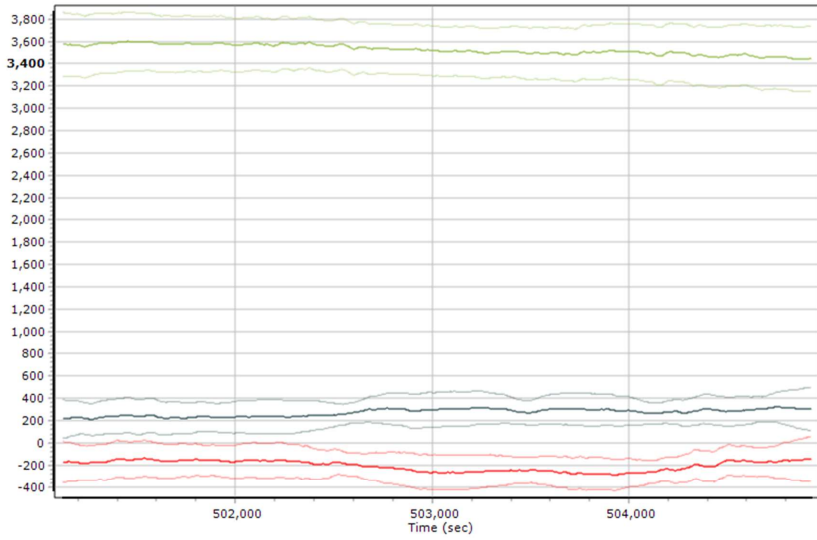
PDOP



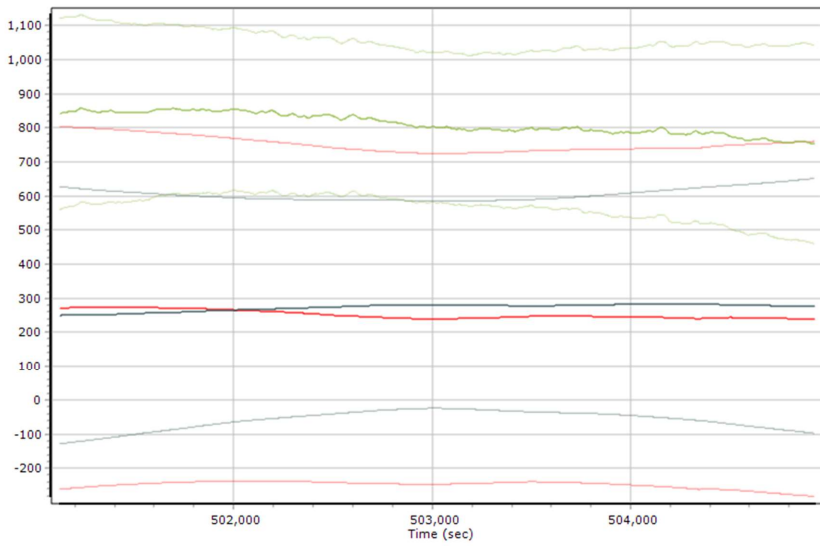
Processing Mode



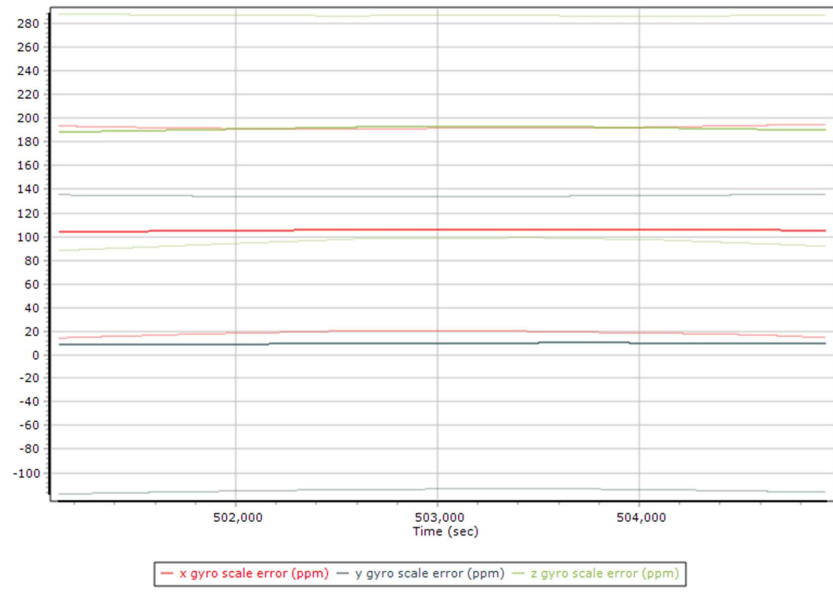
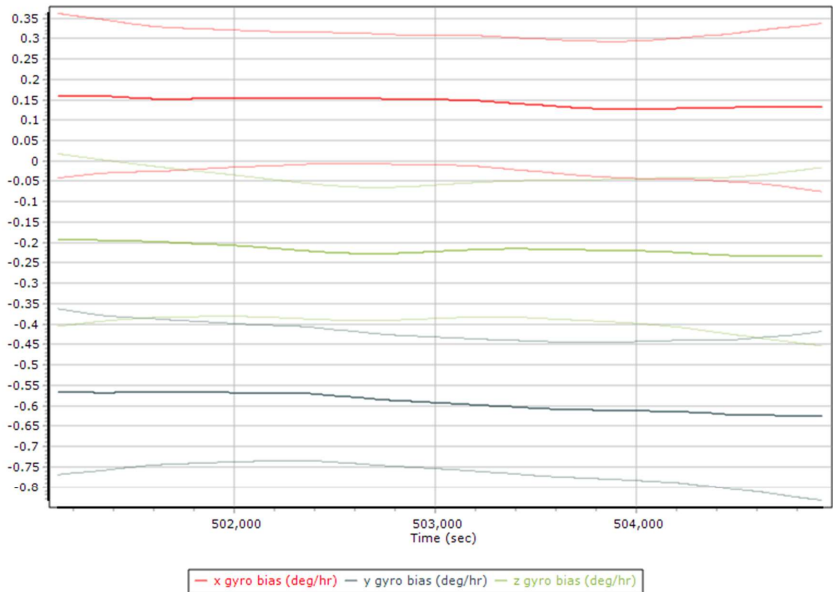
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



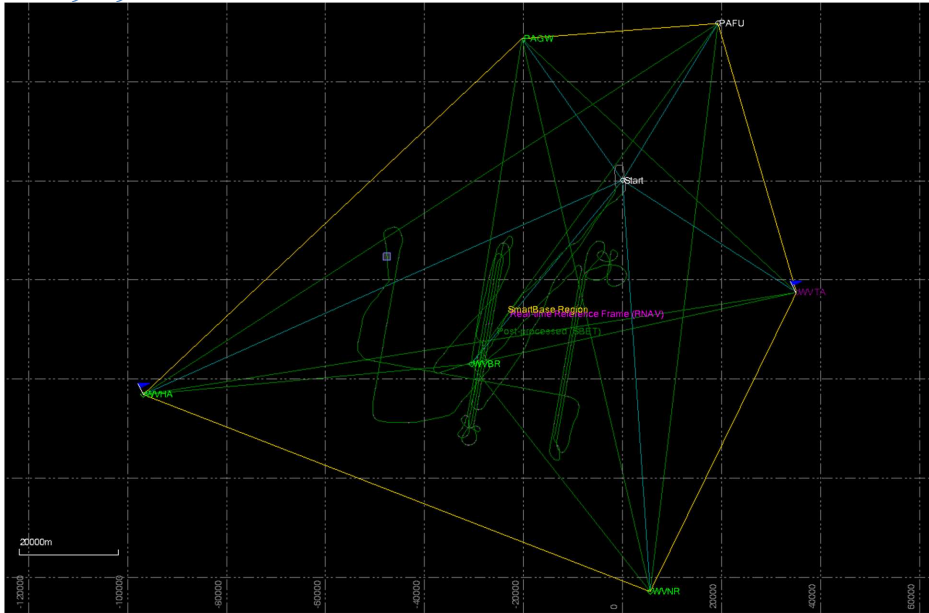
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
|----------------------------|----------------------------------|
| X: 0.034 m | X: 0.000 deg |
| Y: 0.018 m | Y: 0.000 deg |
| Z: -0.155 m | Z: 0.000 deg |

| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
|-------------------------------------|---------------------------------------|
| X: -0.118 m | X: 0.000 deg |
| Y: -0.062 m | Y: 0.000 deg |
| Z: -0.952 m | Z: 0.000 deg |

Standard Deviation: <3cm 10cm 50cm 1m 10m

OK Cancel

Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization

Timing

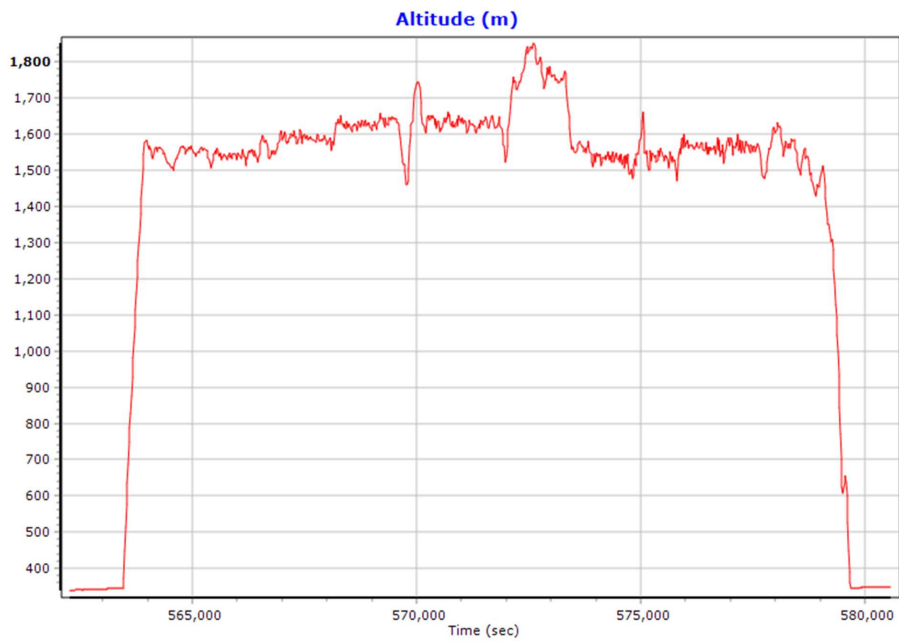
Start: 563541.234 Data: Incr. (sec)

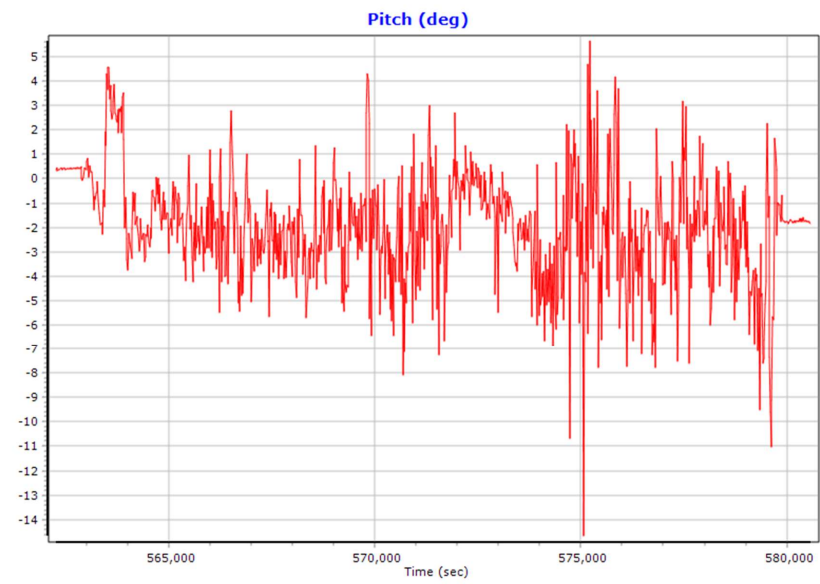
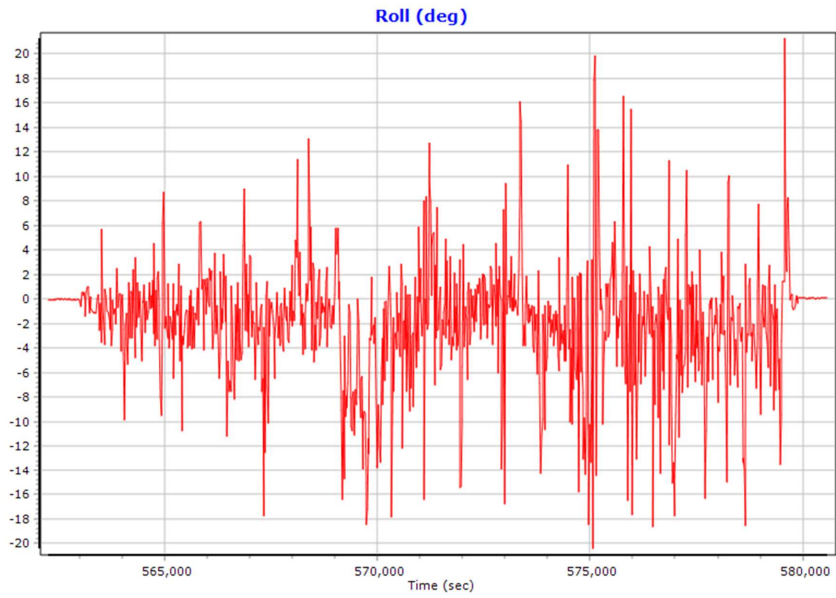
End: 579501.769 Output Record: 0.005000

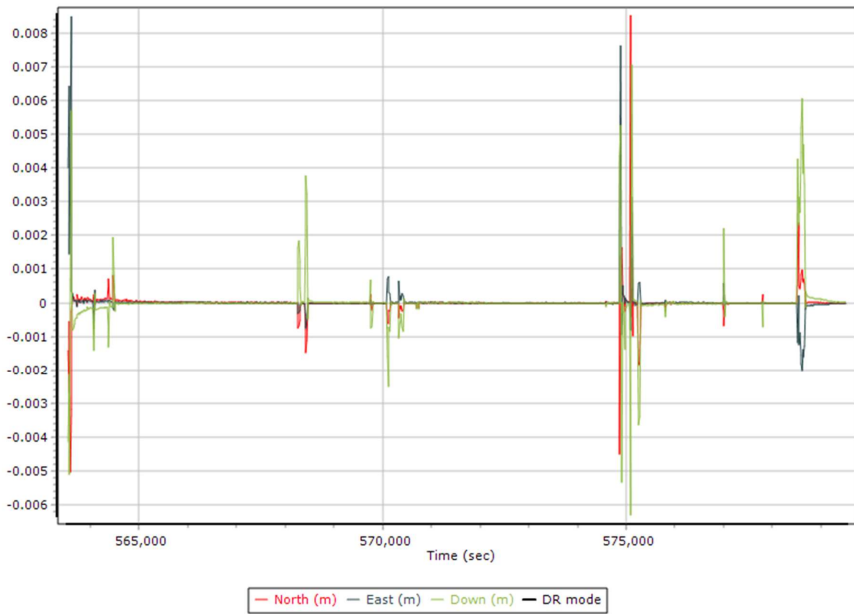
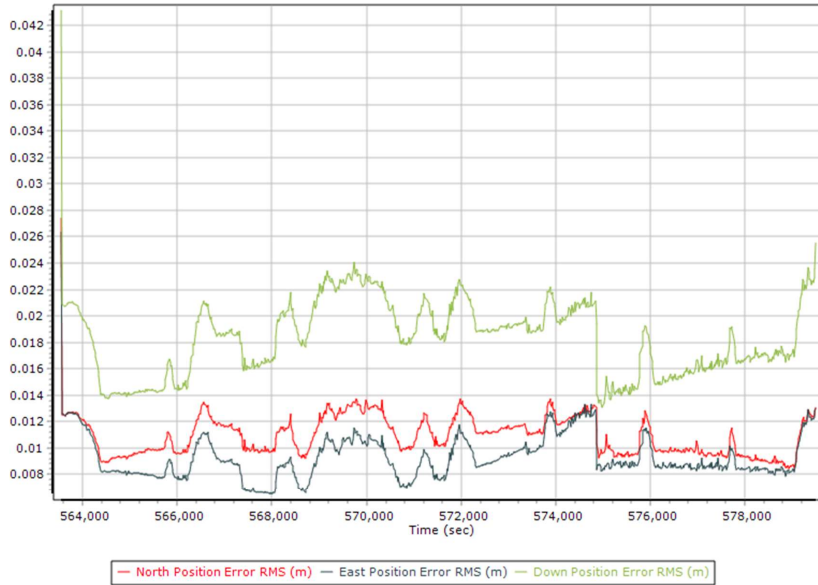
Entire time interval IMU: 0.005000

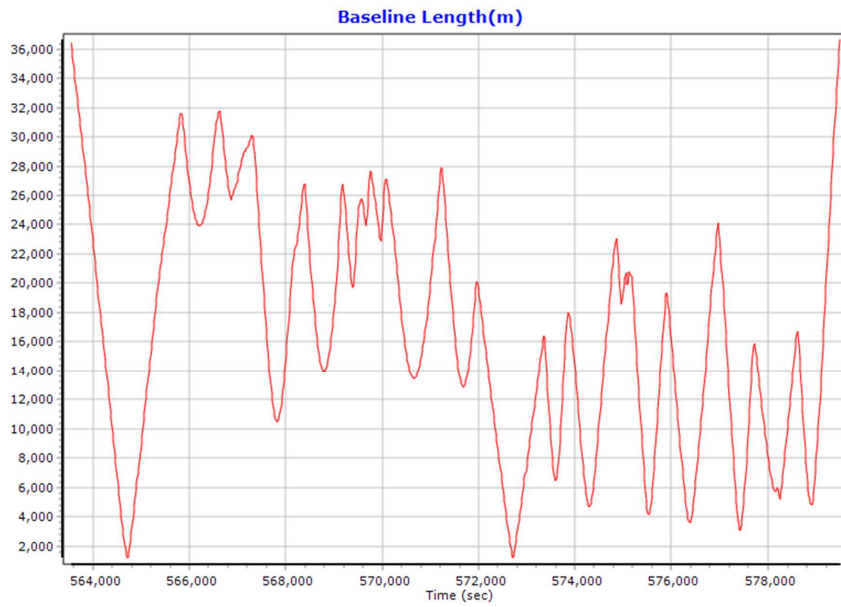
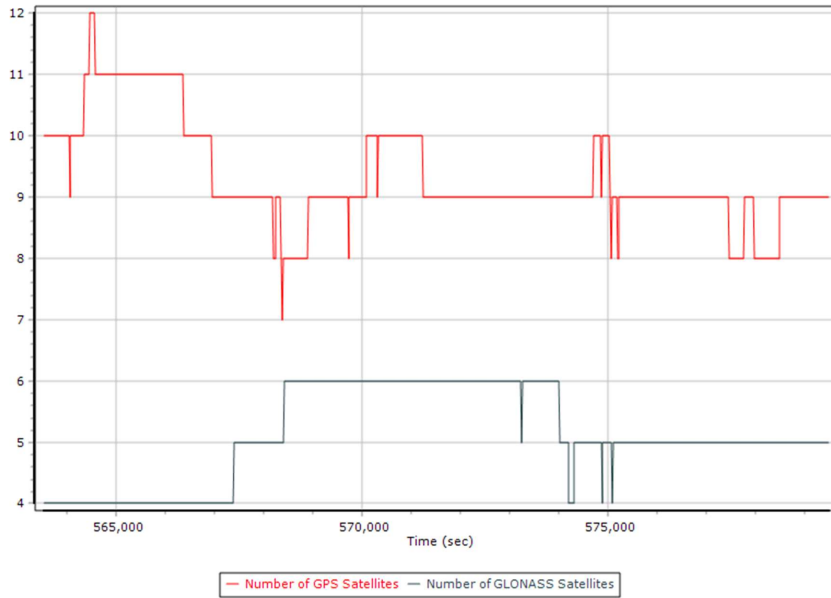
Seconds of start week Primary GNSS: 1.000000

UTC Offset: 18.000







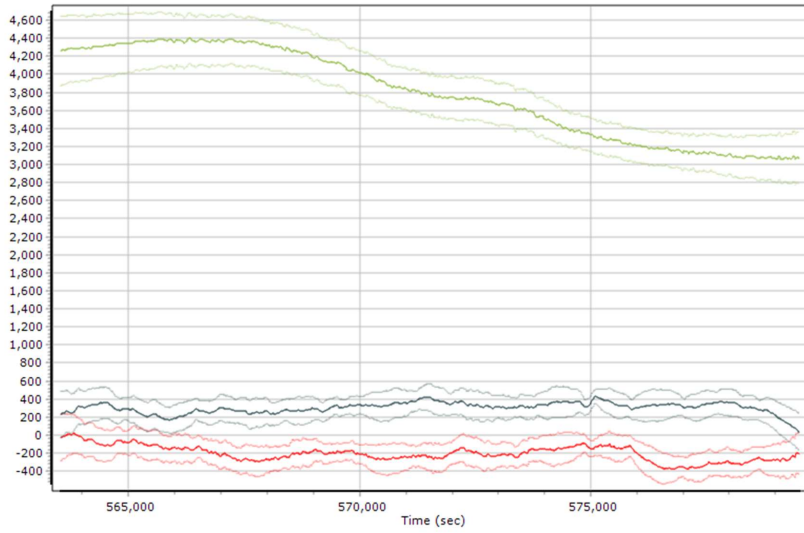


PDOP

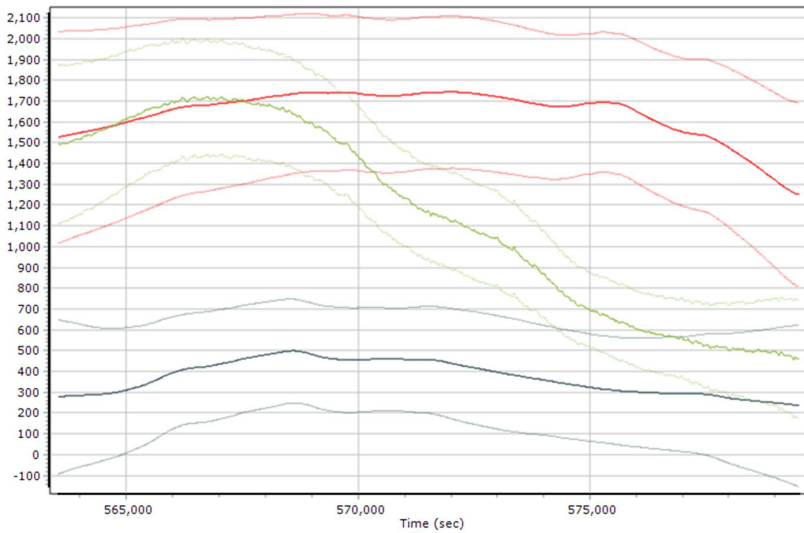


Processing Mode

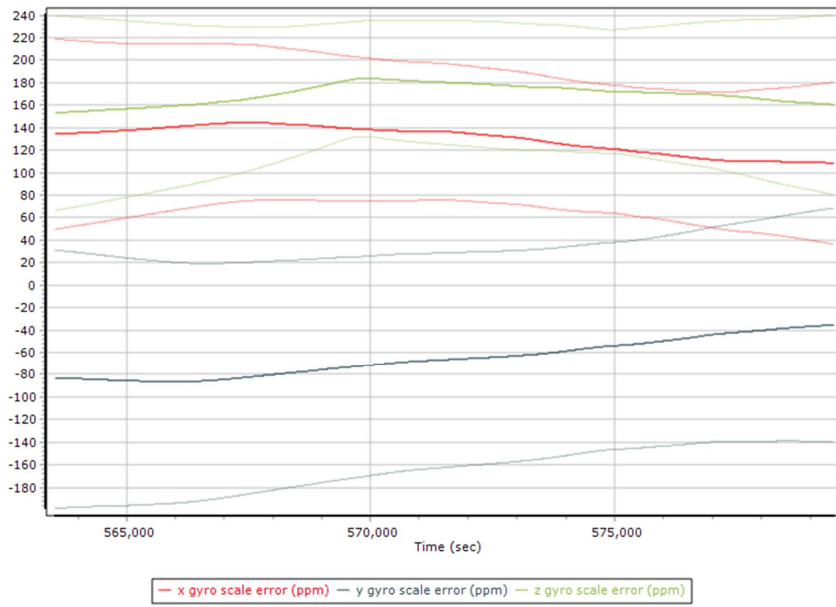
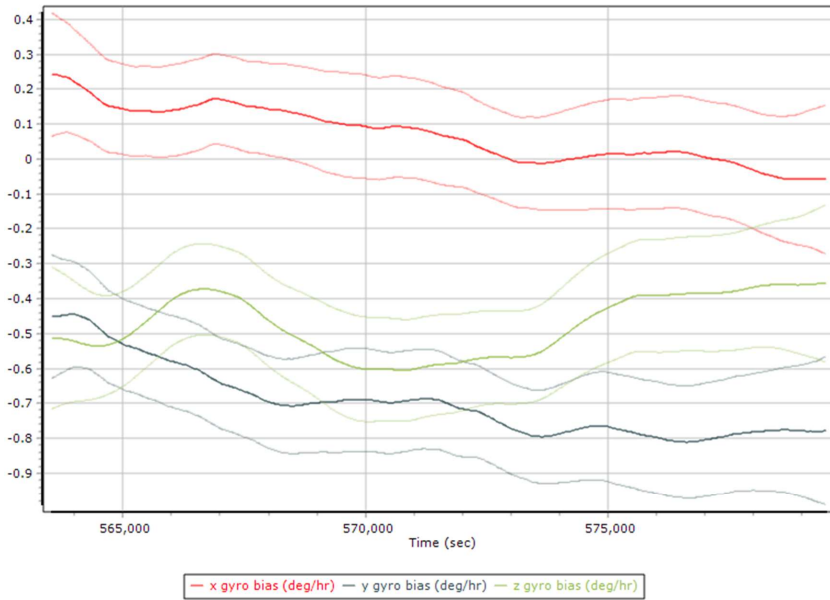




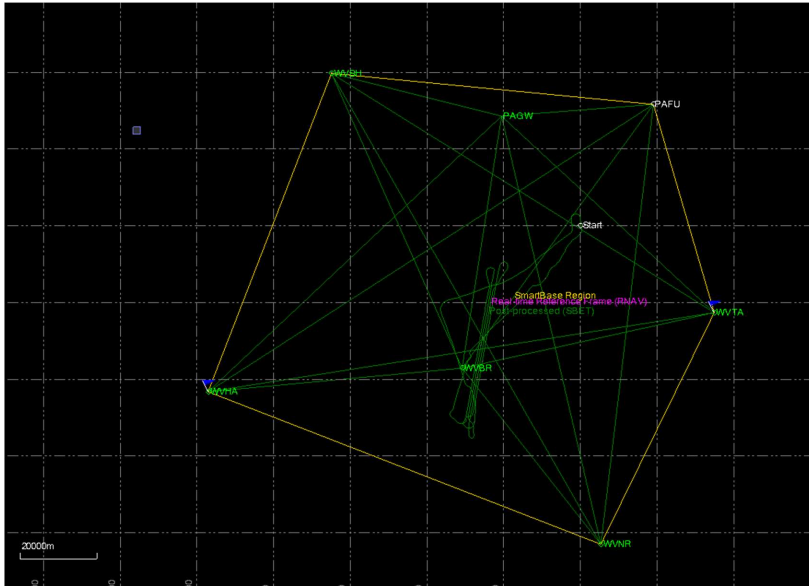
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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| | | | |
|-------------------------------------|---------------------------------------|---------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.118 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.062 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.952 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | <input type="text" value="3cm"/> | | |
| | <3cm 10cm 50cm 1m 10m | | |

Timing

Start: 584816.000

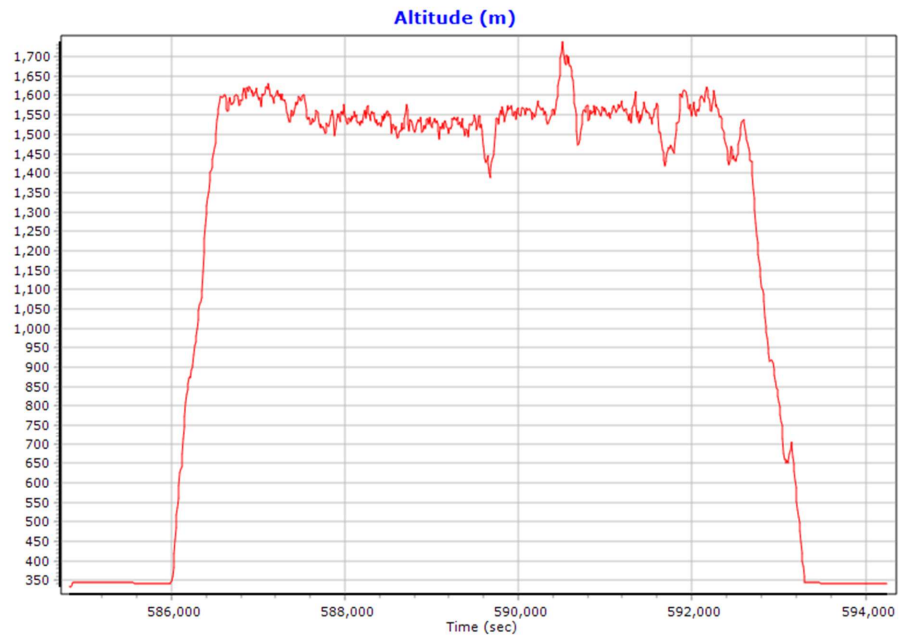
End: 594248.000

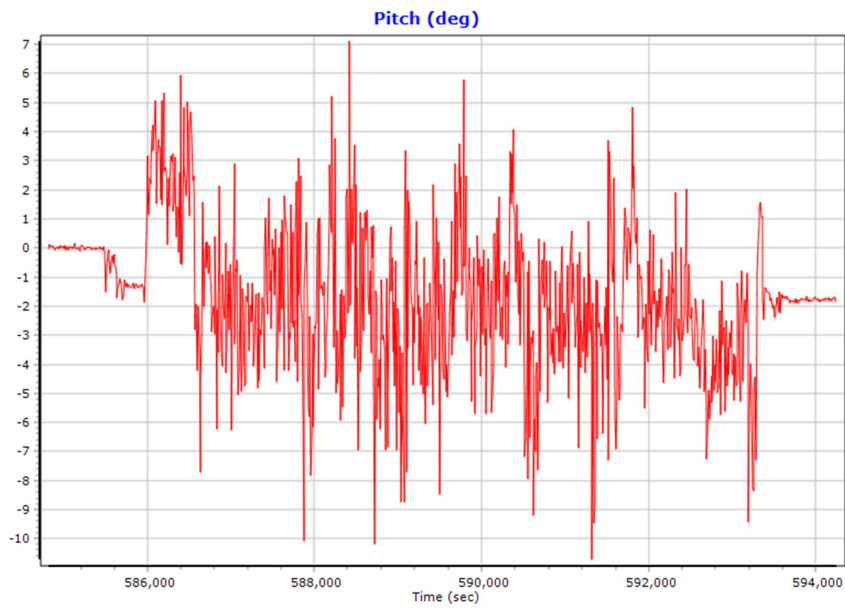
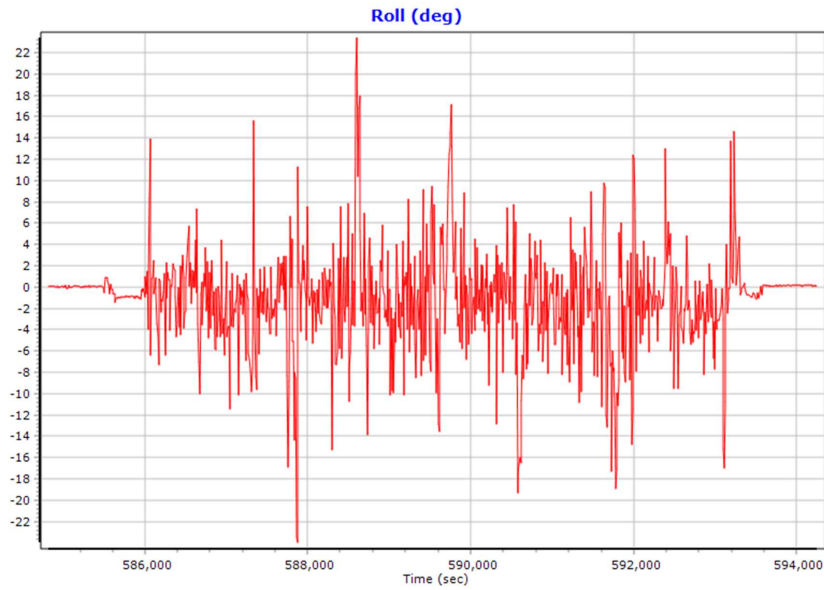
Entire time interval

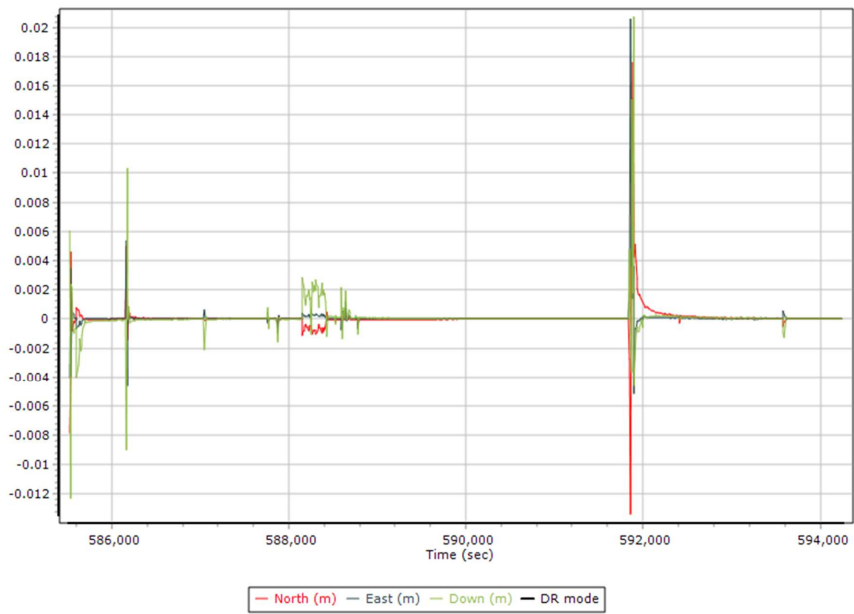
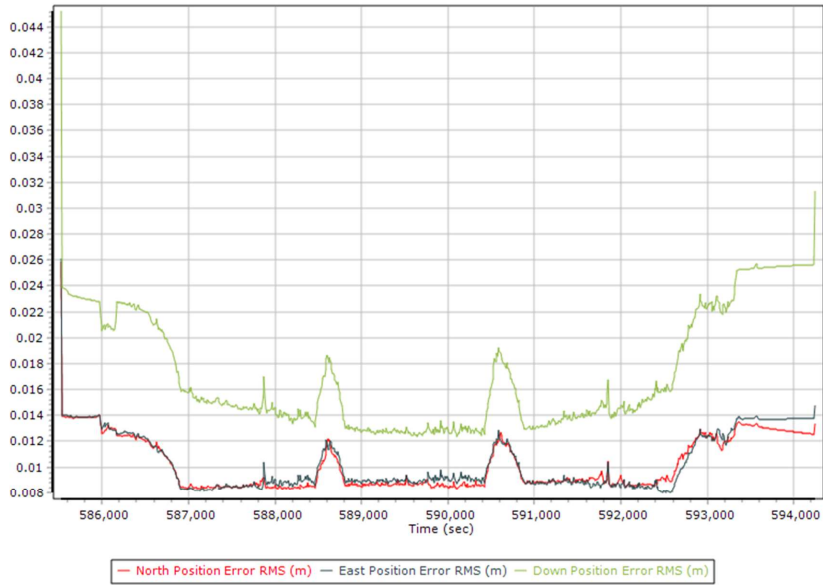
Seconds of start week

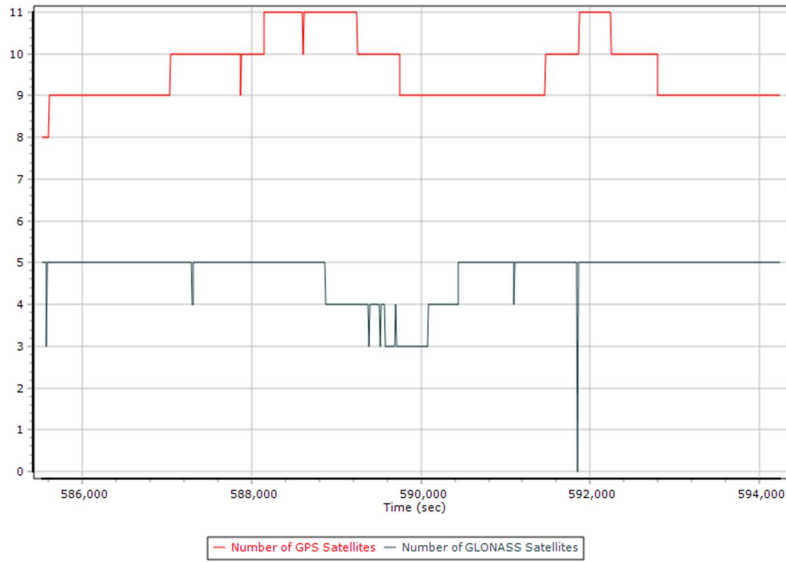
UTC Offset: 18.000

| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

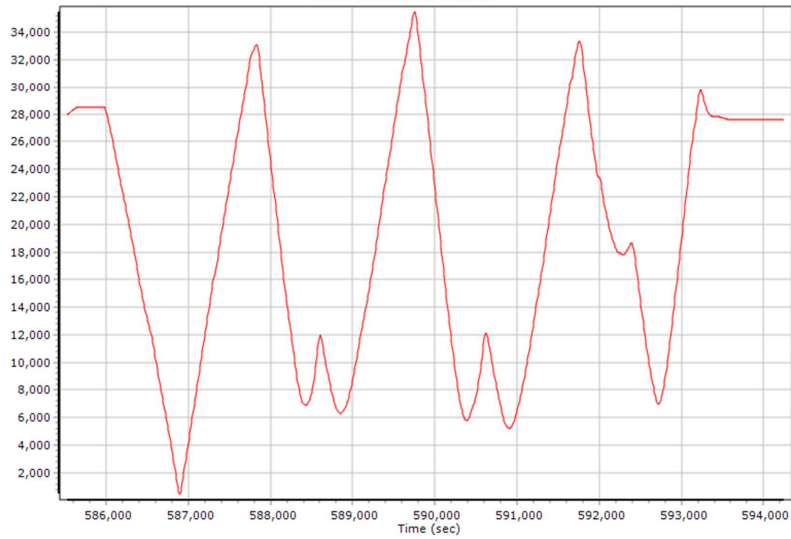


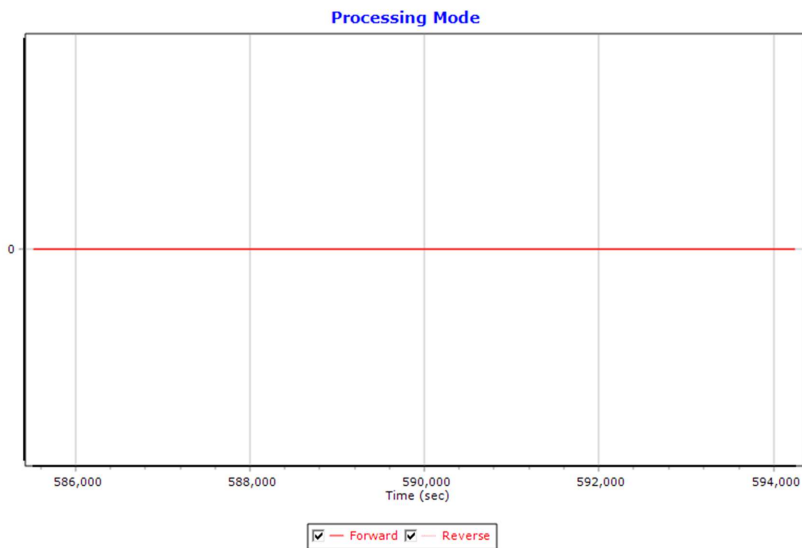
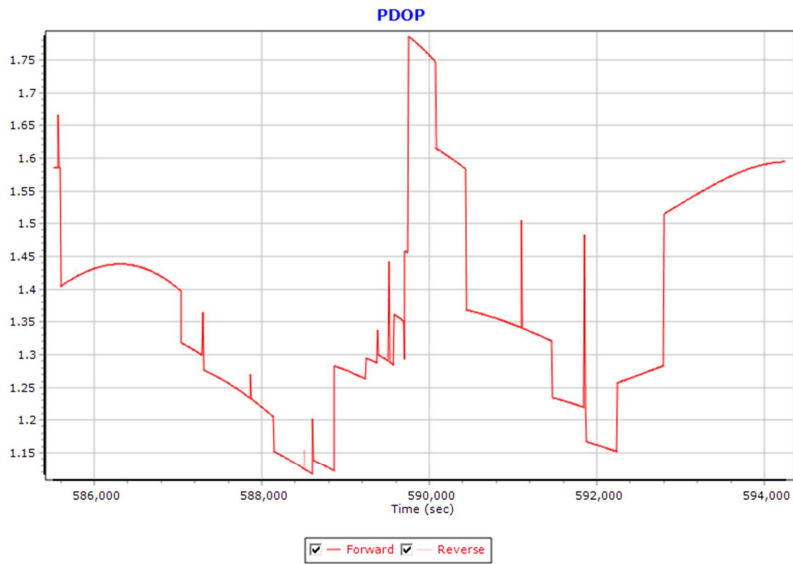




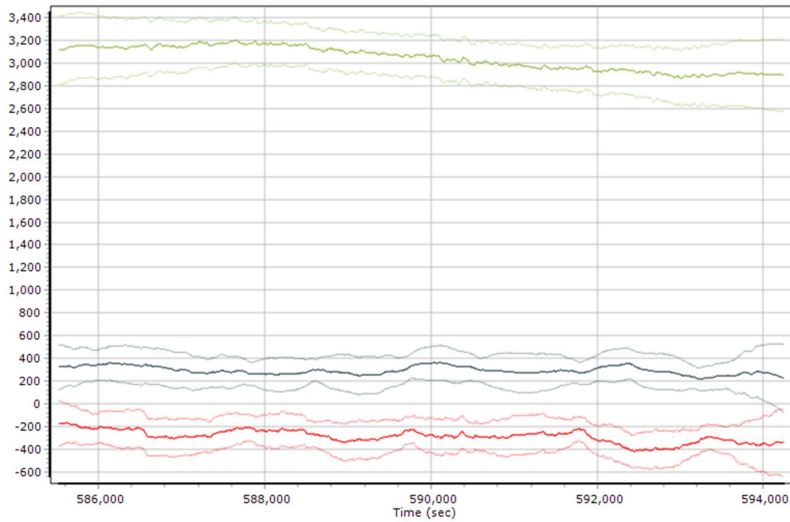


Baseline Length(m)

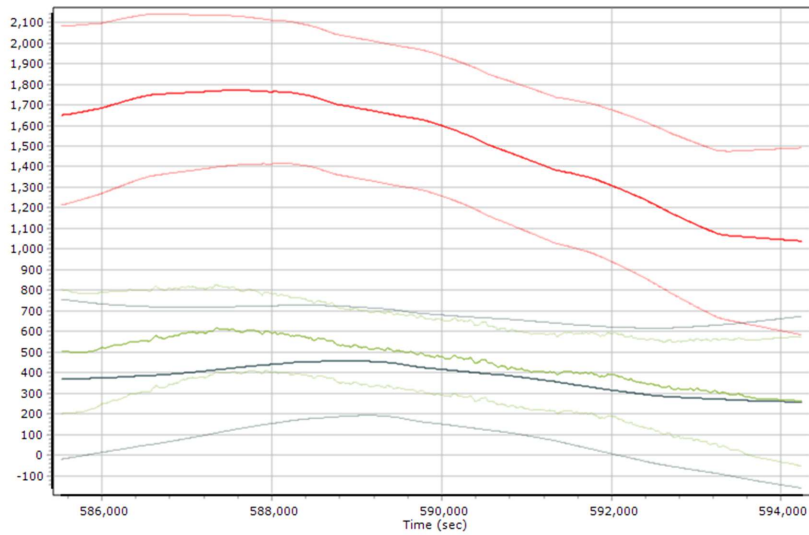




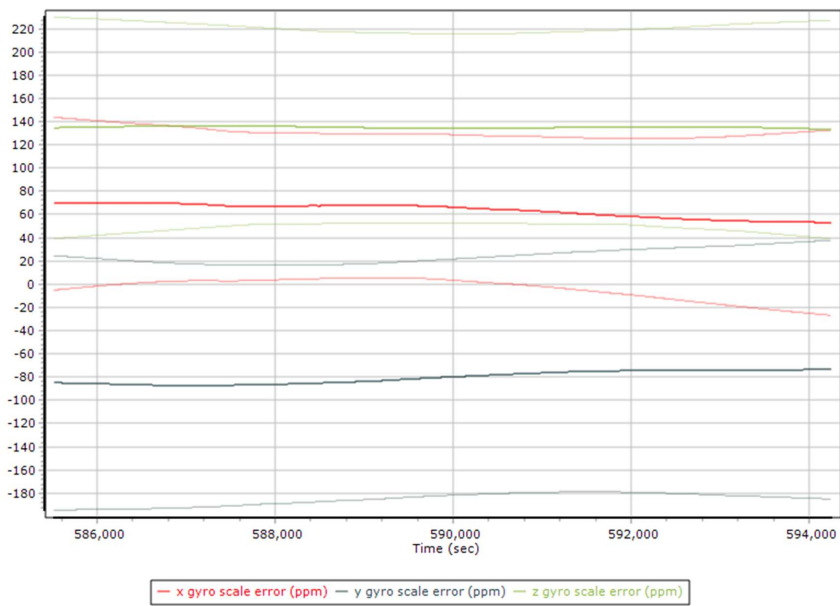
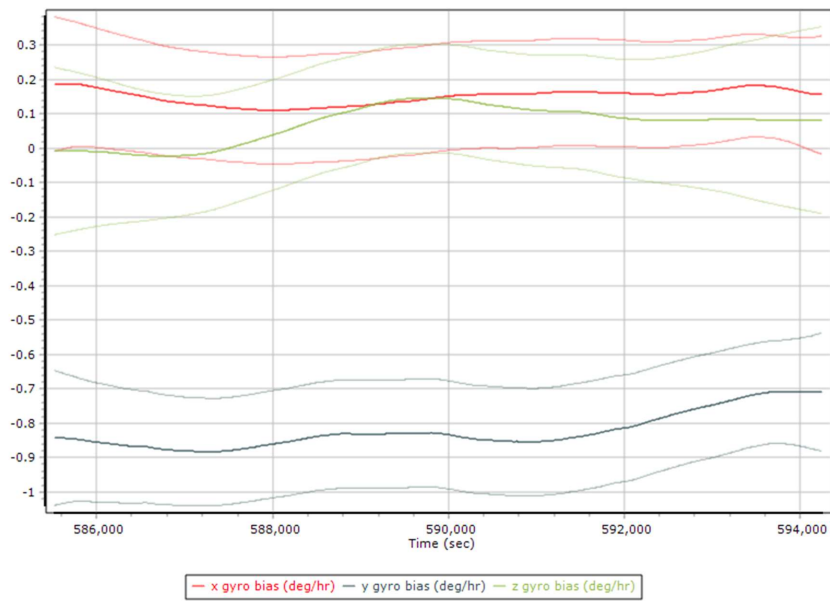
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



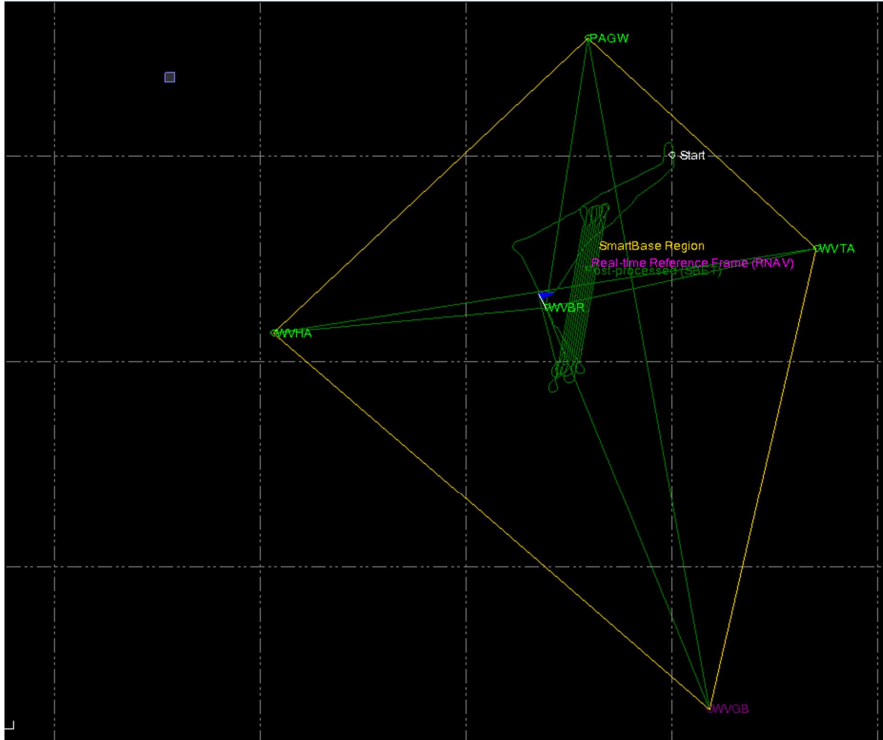
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



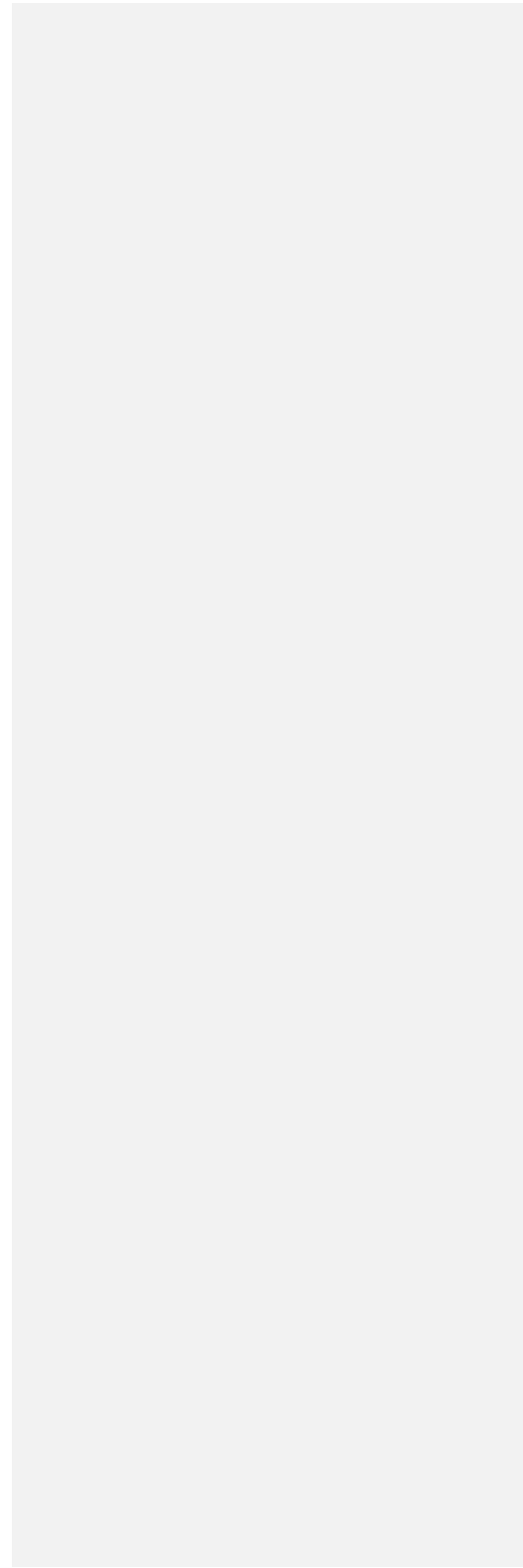
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



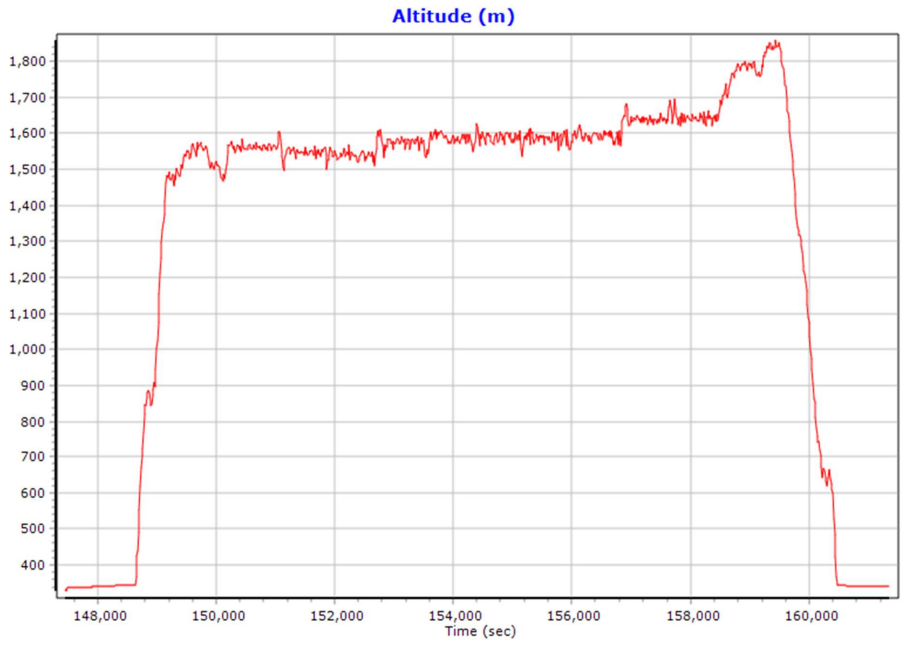
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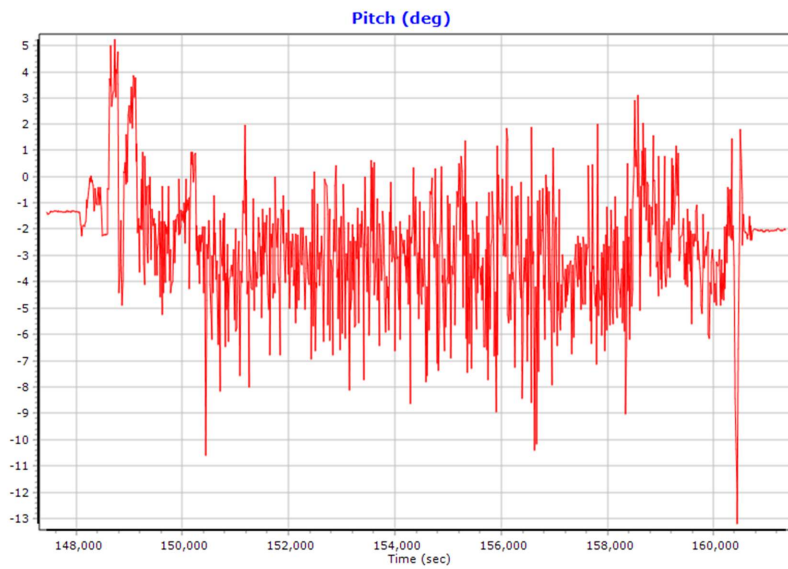
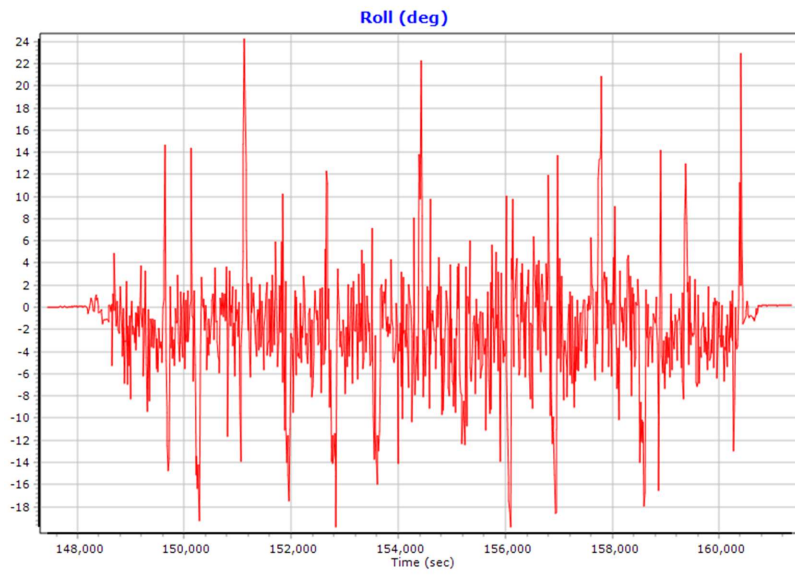


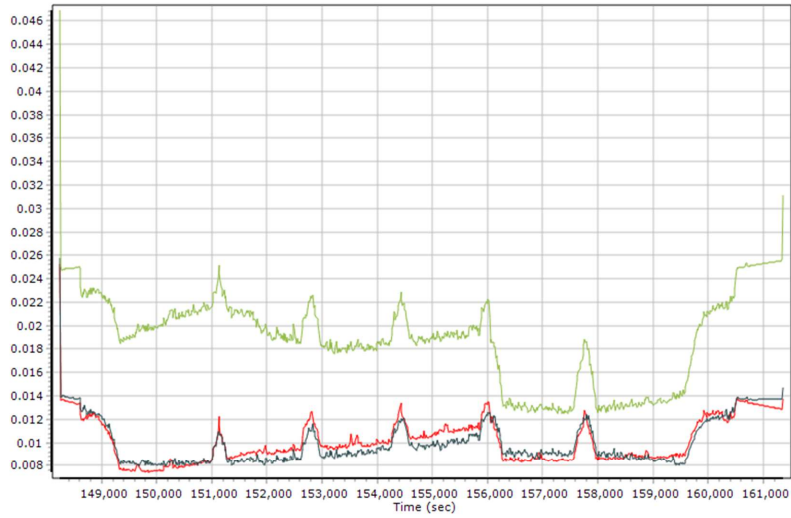
| | | | |
|-------------------------------------|---------------------------------------|---------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.118 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.062 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.952 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | <input type="range" value="30"/> | | |
| | <3cm 10cm 50cm 1m 10m | | |



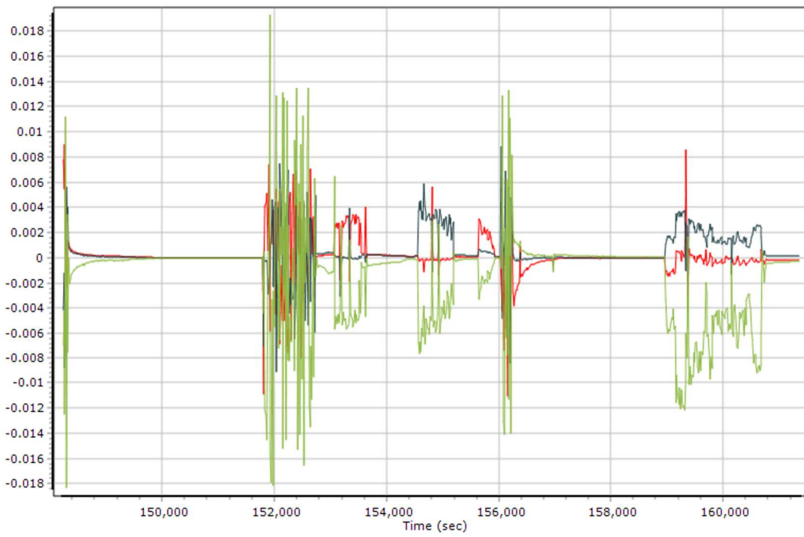
| | | | |
|--------------------------------------------|---------------------------------------|----------------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.118 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.062 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.952 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | <input type="text" value="3cm"/> | | |
| | <3cm 10cm 50cm 1m 10m | | |



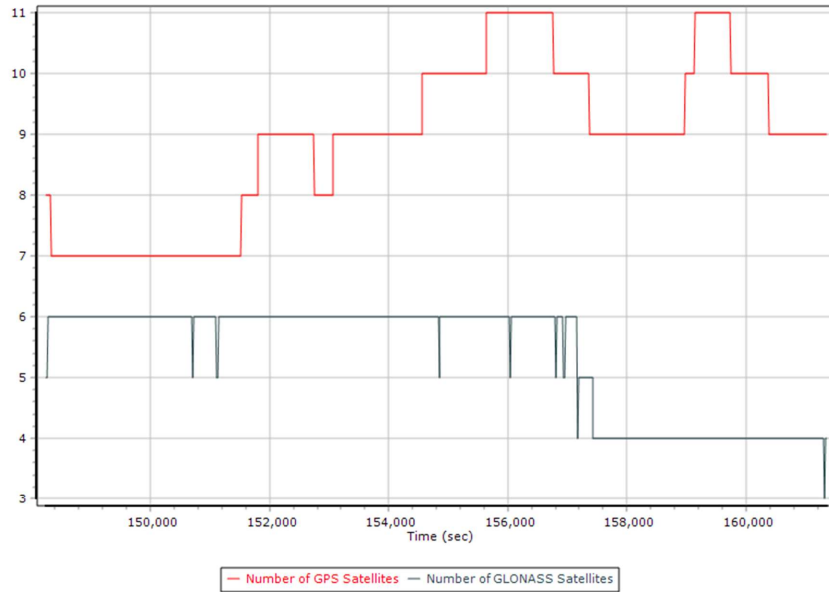




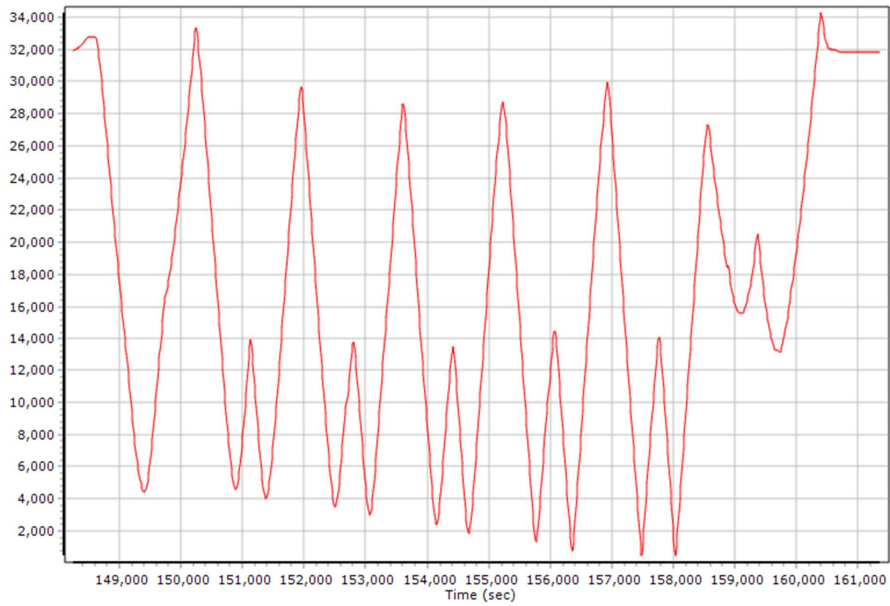
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



— North (m) — East (m) — Down (m) — DR mode



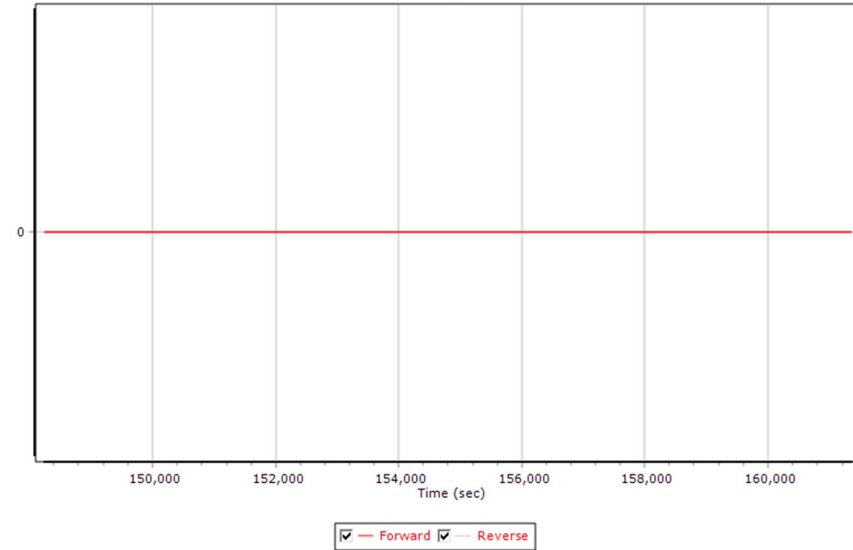
Baseline Length(m)



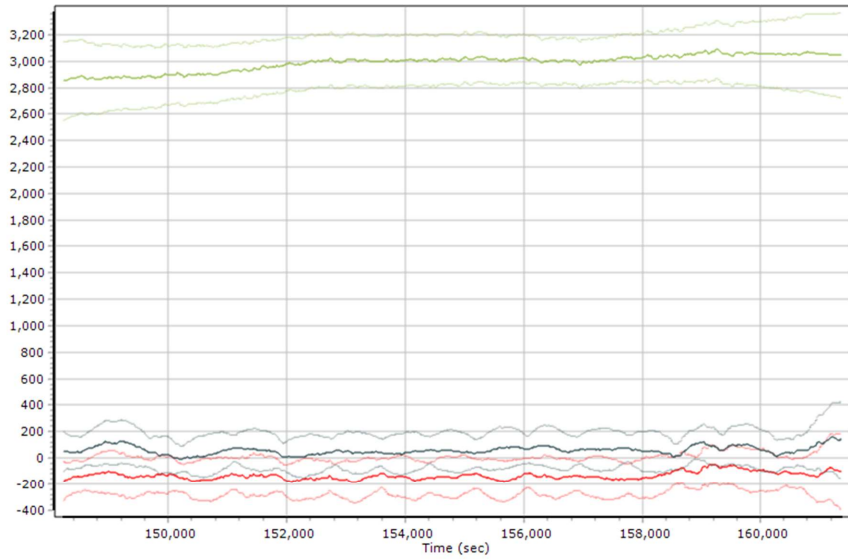
PDOP



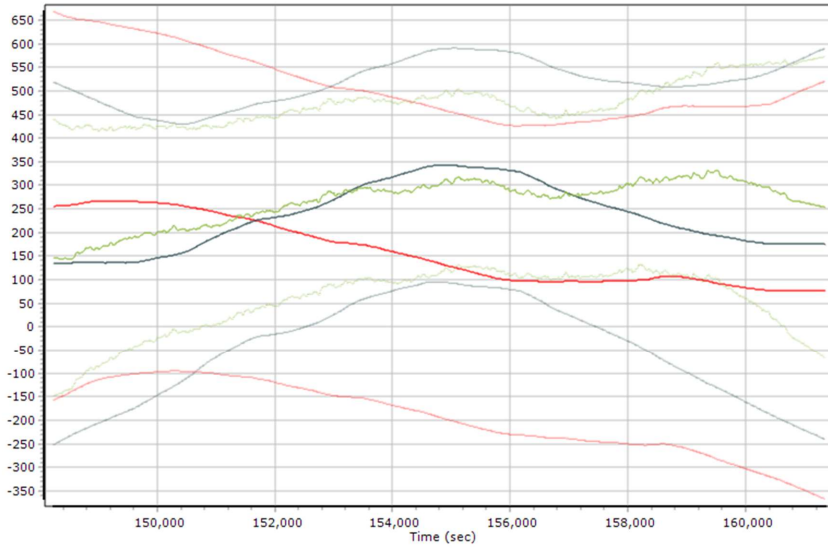
Processing Mode



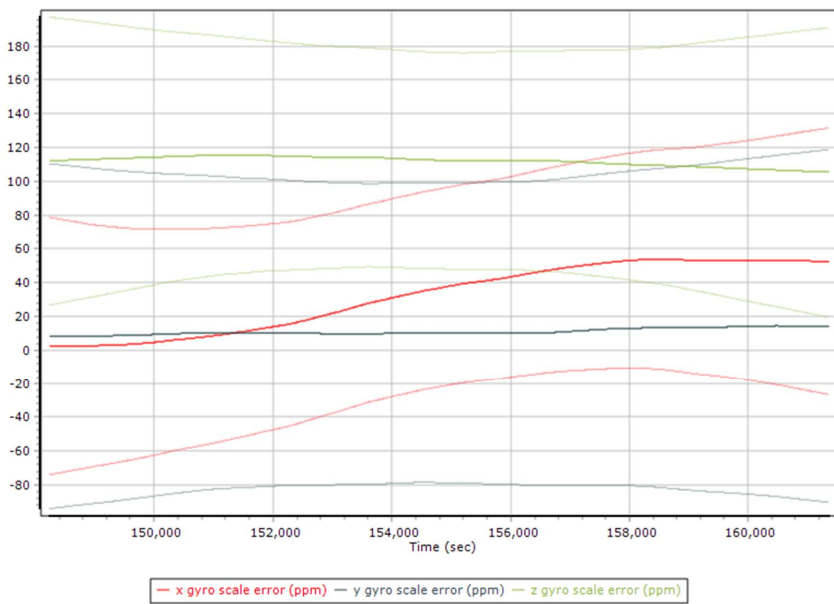
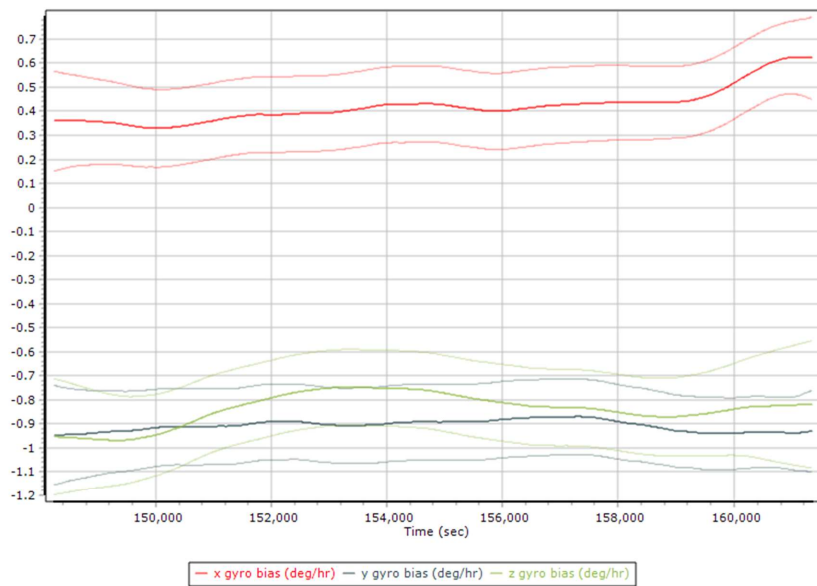
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



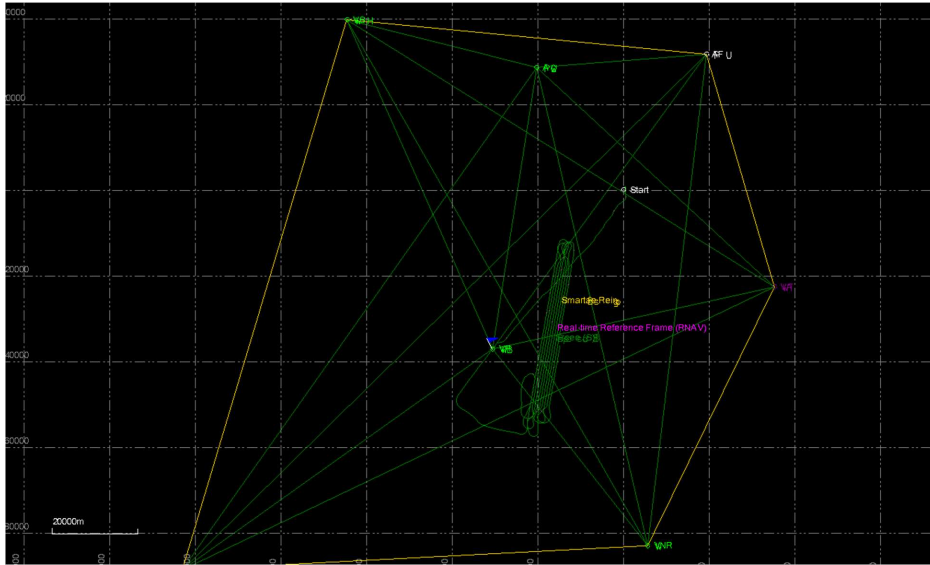
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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Project Settings [Close]

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
|----------------------------|----------------------------------|
| X: 0.034 m | X: 0.000 deg |
| Y: 0.018 m | Y: 0.000 deg |
| Z: -0.155 m | Z: 0.000 deg |

| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
|-------------------------------------|---------------------------------------|
| X: -0.118 m | X: 0.000 deg |
| Y: -0.062 m | Y: 0.000 deg |
| Z: -0.952 m | Z: 0.000 deg |

Standard Deviation: [Slider] <3cm 10cm 50cm 1m 10m

[OK] [Cancel]

Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
- Timing

Timing

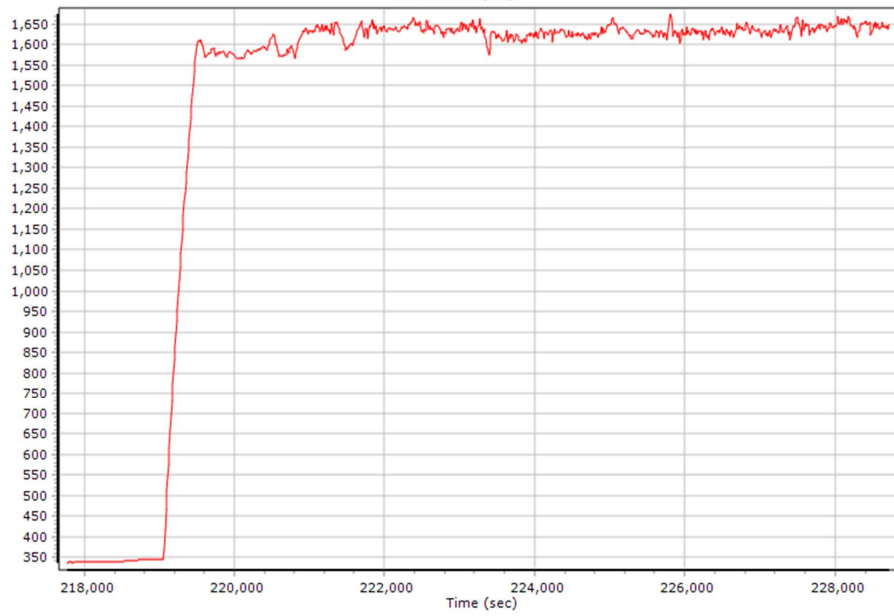
Start: 217773.000
End: 228722.000

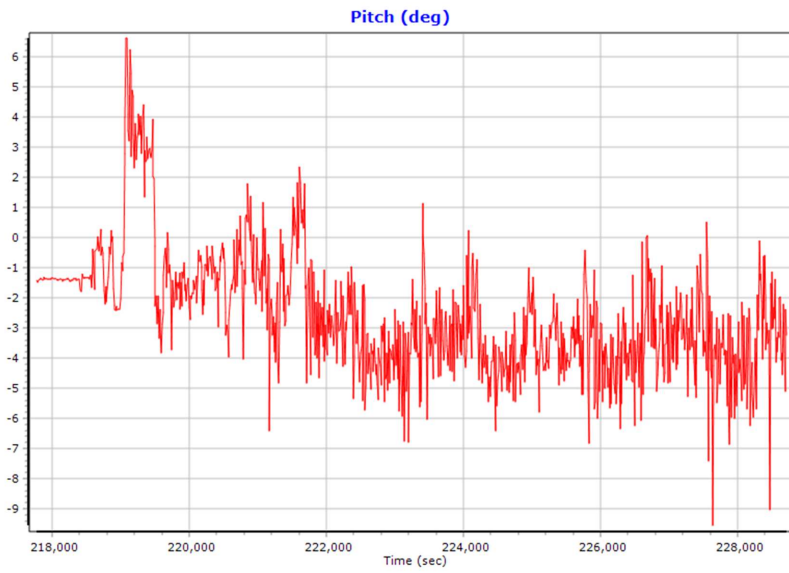
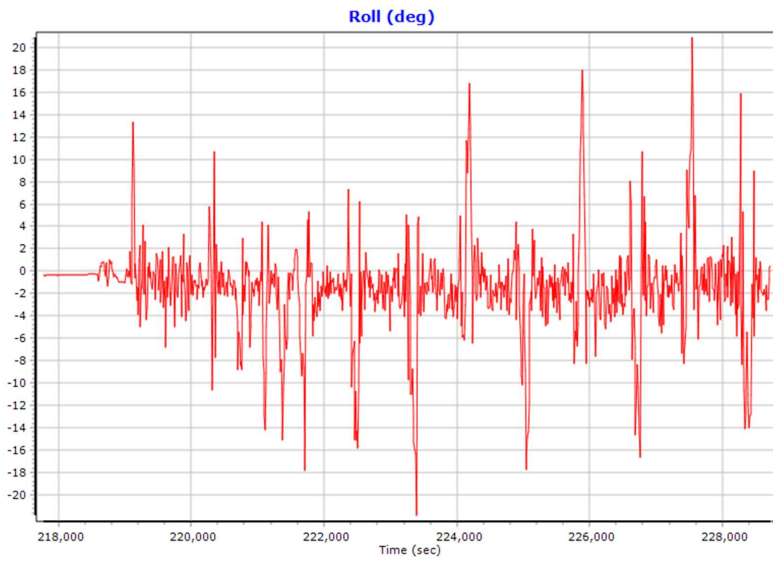
Entire time interval
 Seconds of start week

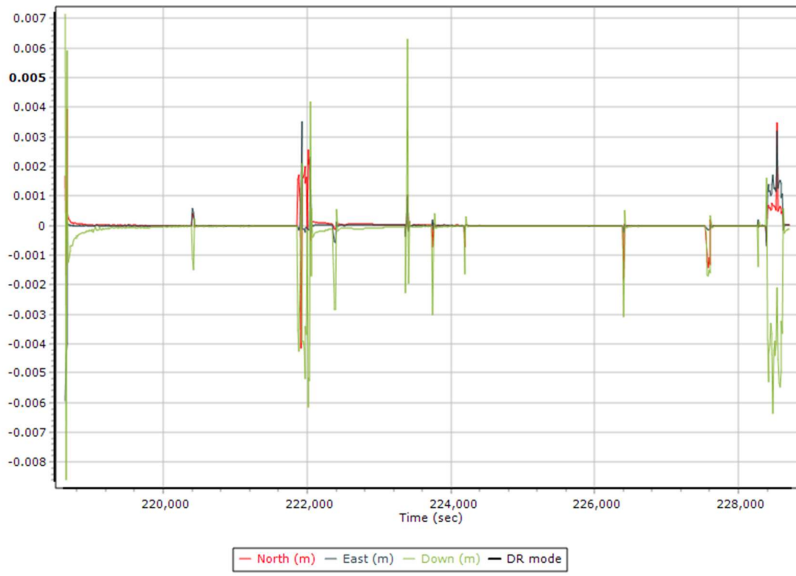
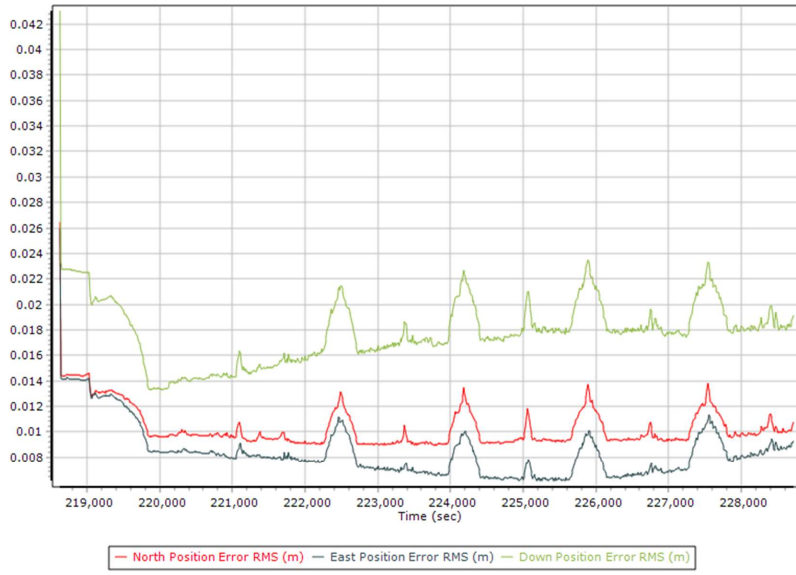
UTC Offset: 18.000

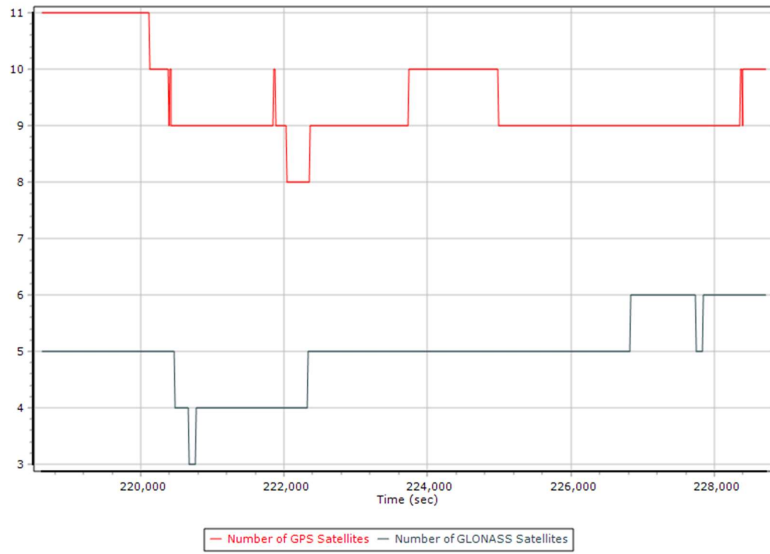
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

Altitude (m)

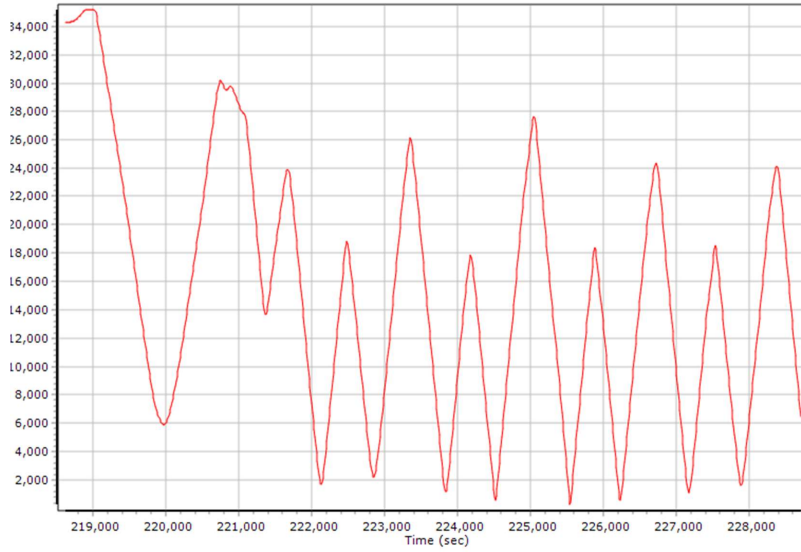




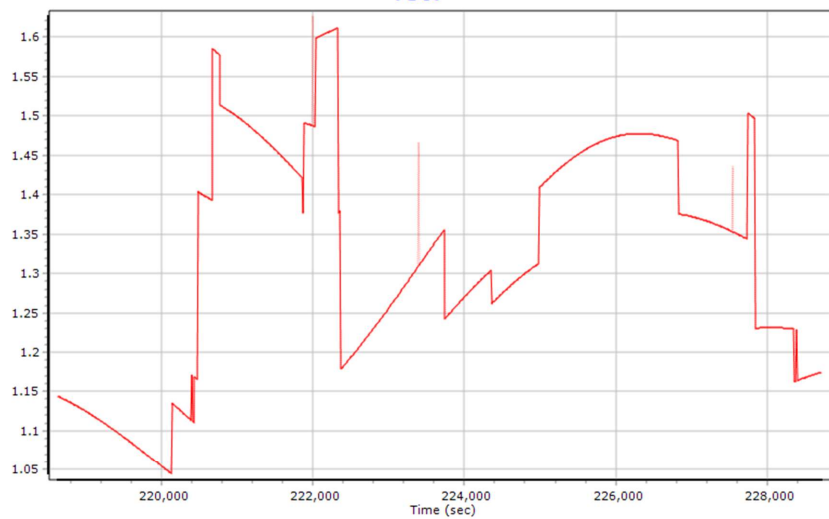




Baseline Length(m)

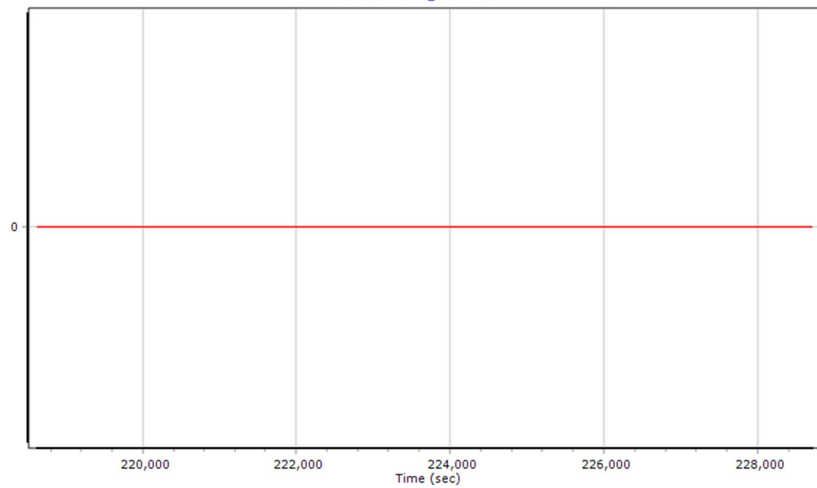


PDOP



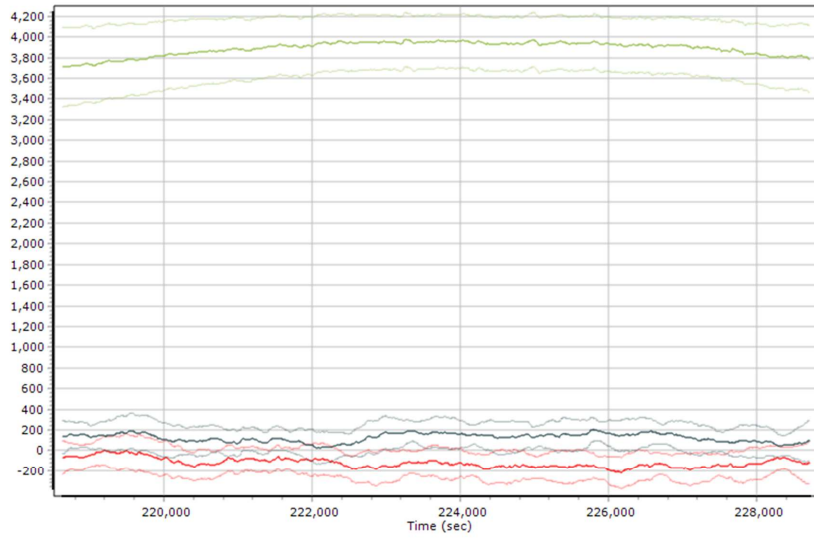
Forward Reverse

Processing Mode

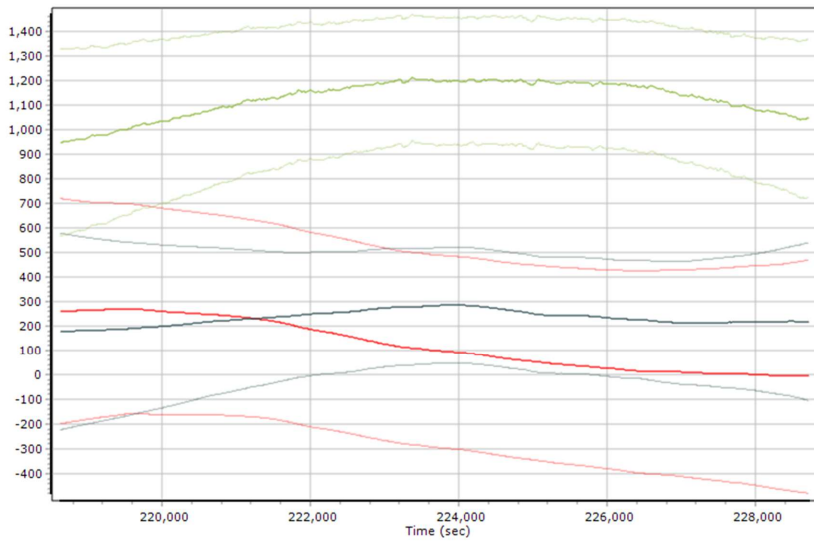


Forward Reverse

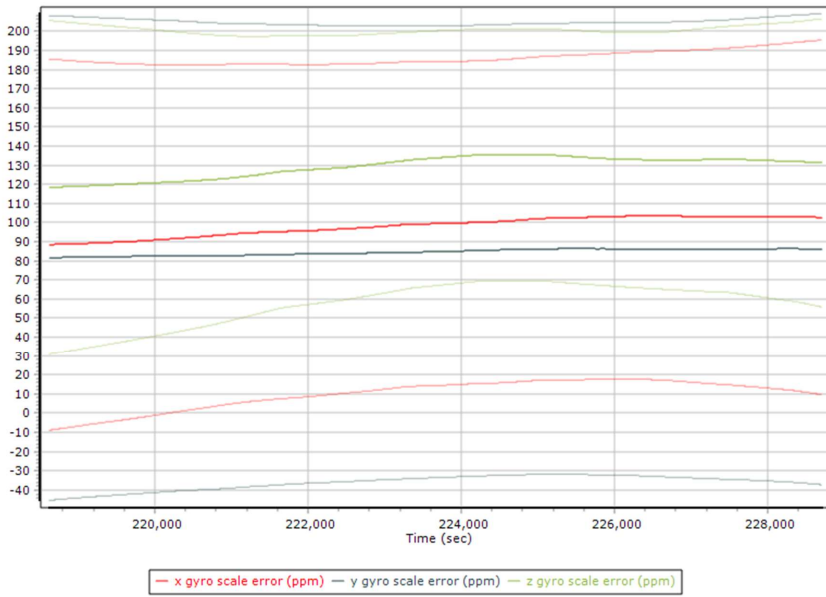
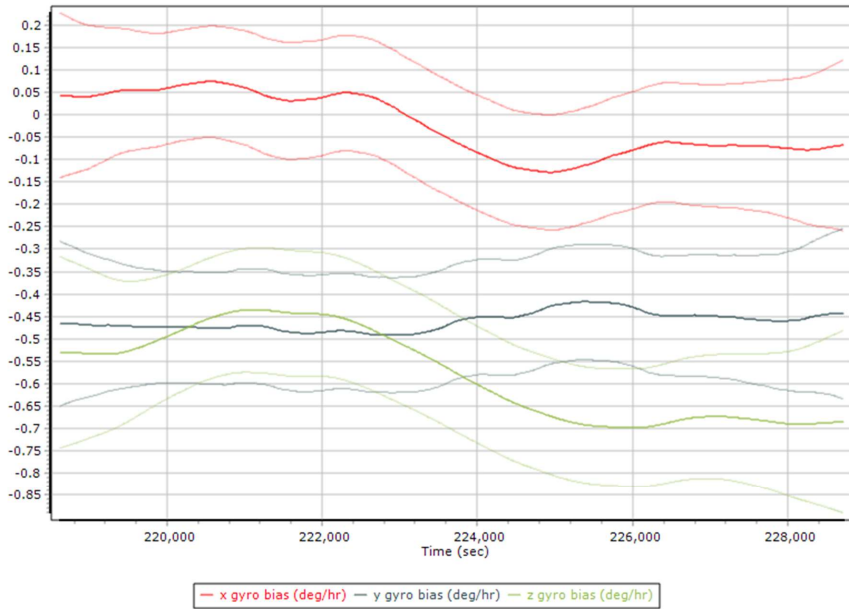
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



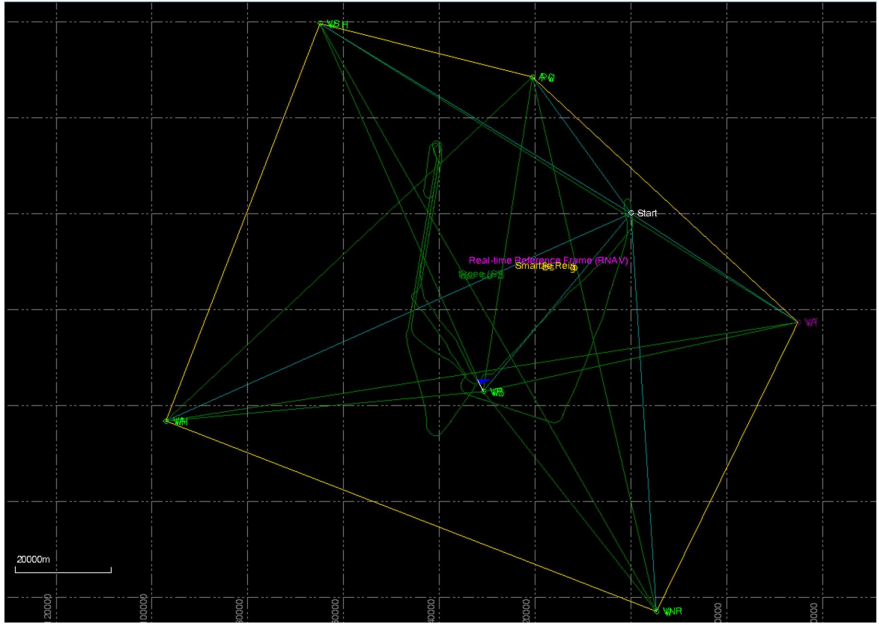
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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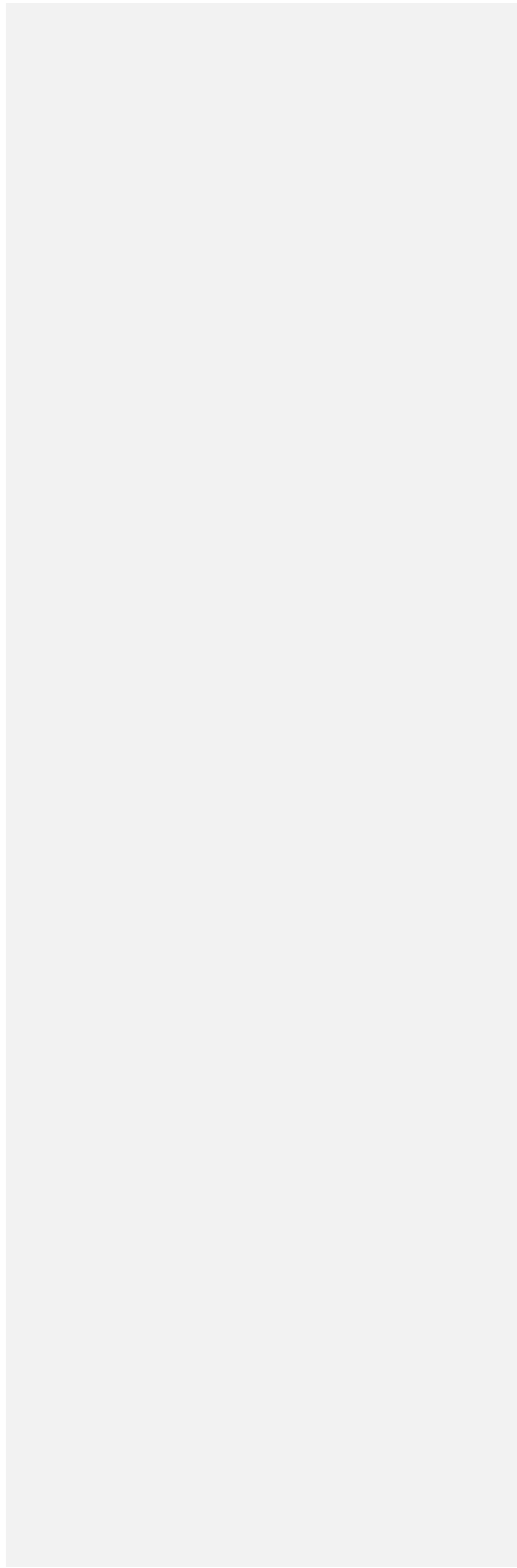
General Information

- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
 - Export
 - Camera
 - LiDAR
 - SAR

| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
|------------------------------------------|-------------------------------------------|
| X: <input type="text" value="0.034 m"/> | X: <input type="text" value="0.000 deg"/> |
| Y: <input type="text" value="0.018 m"/> | Y: <input type="text" value="0.000 deg"/> |
| Z: <input type="text" value="-0.155 m"/> | Z: <input type="text" value="0.000 deg"/> |

| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
|------------------------------------------|-------------------------------------------|
| X: <input type="text" value="-0.118 m"/> | X: <input type="text" value="0.000 deg"/> |
| Y: <input type="text" value="-0.062 m"/> | Y: <input type="text" value="0.000 deg"/> |
| Z: <input type="text" value="-0.952 m"/> | Z: <input type="text" value="0.000 deg"/> |

Standard Deviation:



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export

Timing

Start: 239252.000

End: 249527.000

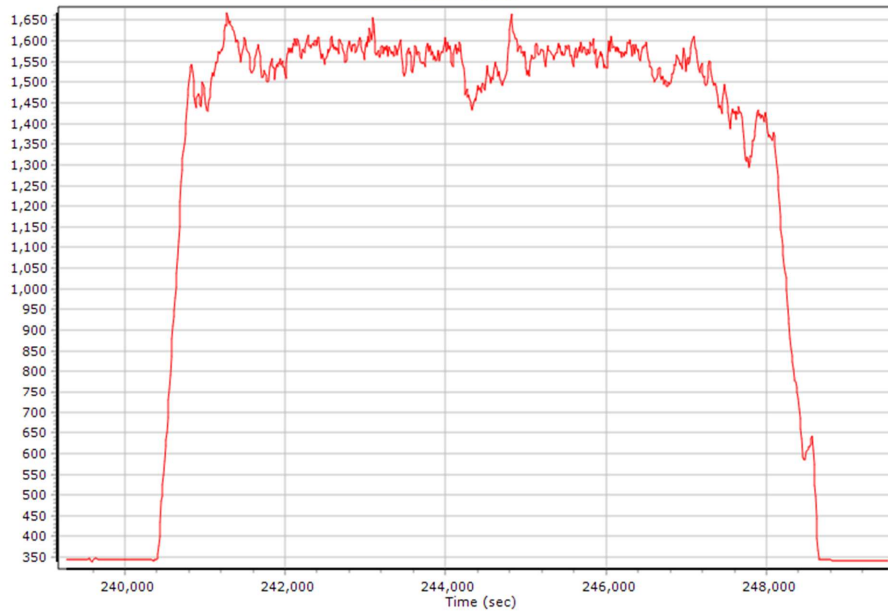
Entire time interval

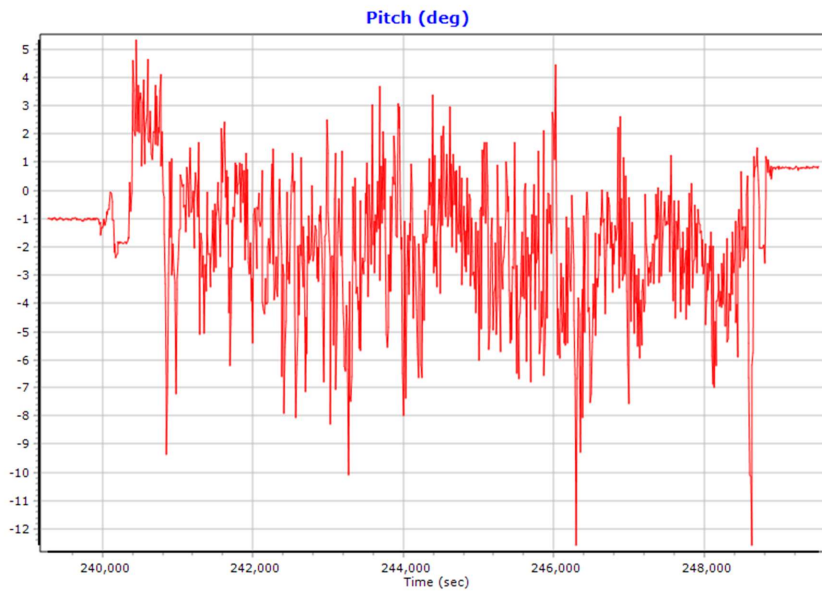
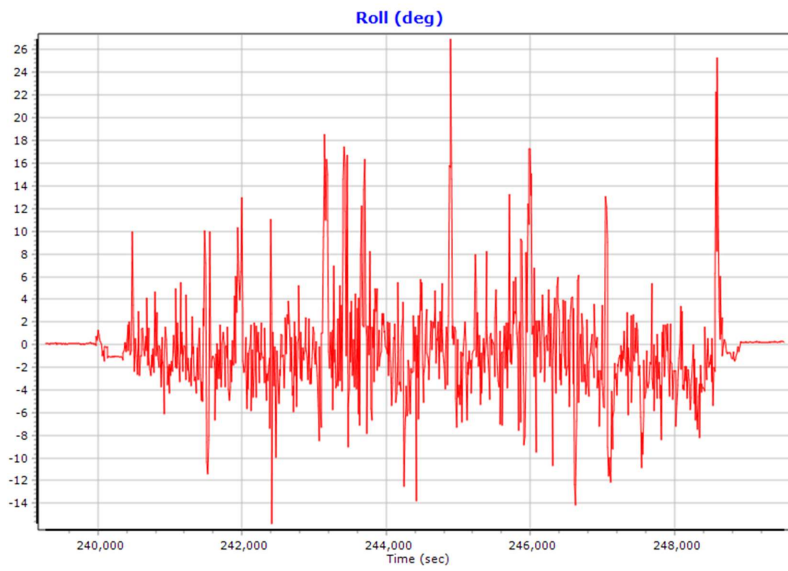
Seconds of start week

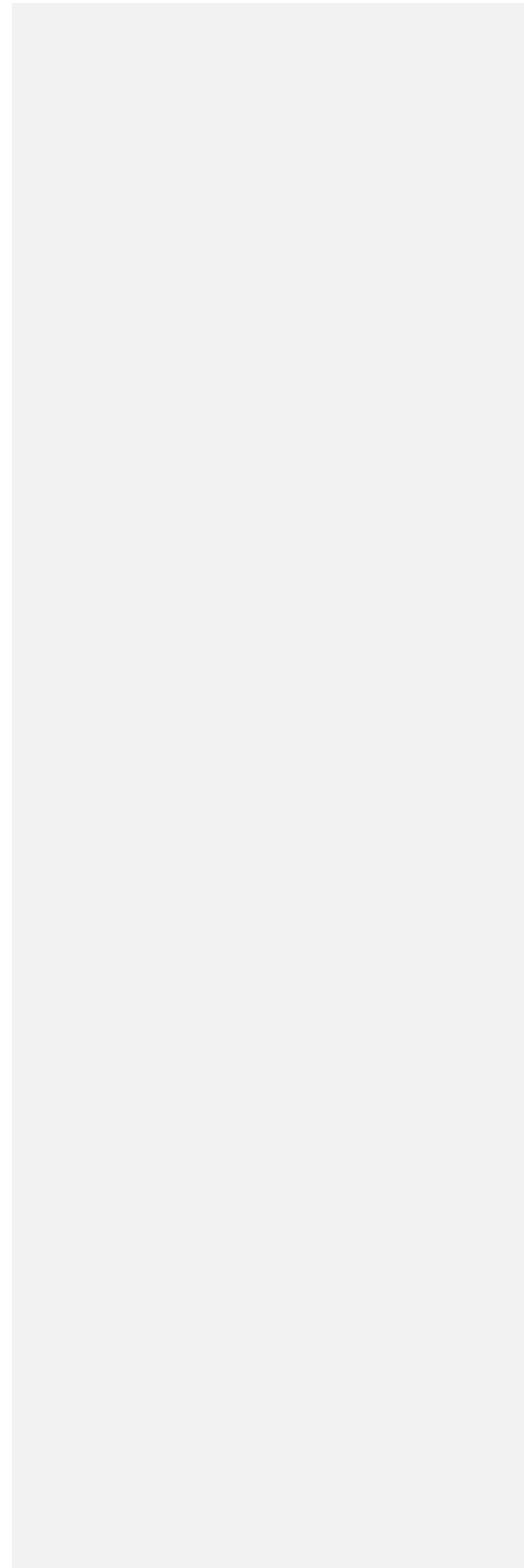
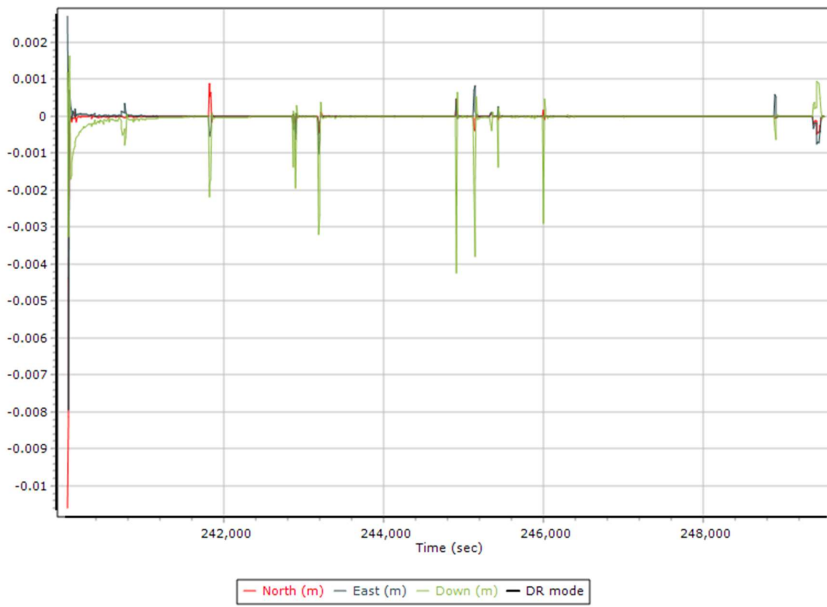
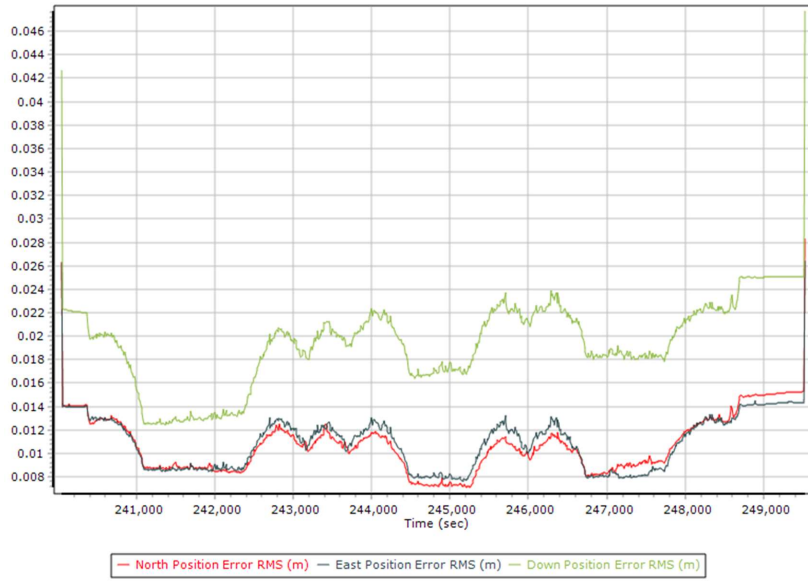
UTC Offset: 18.000

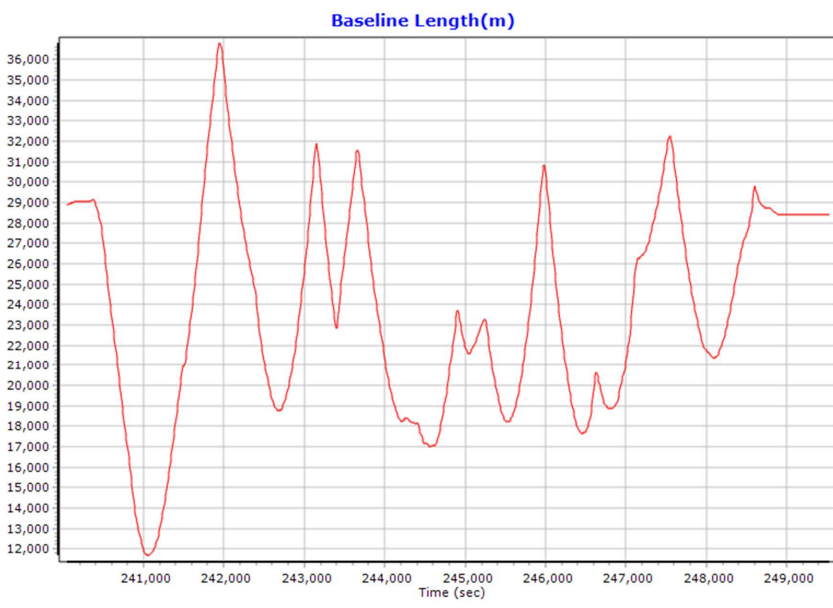
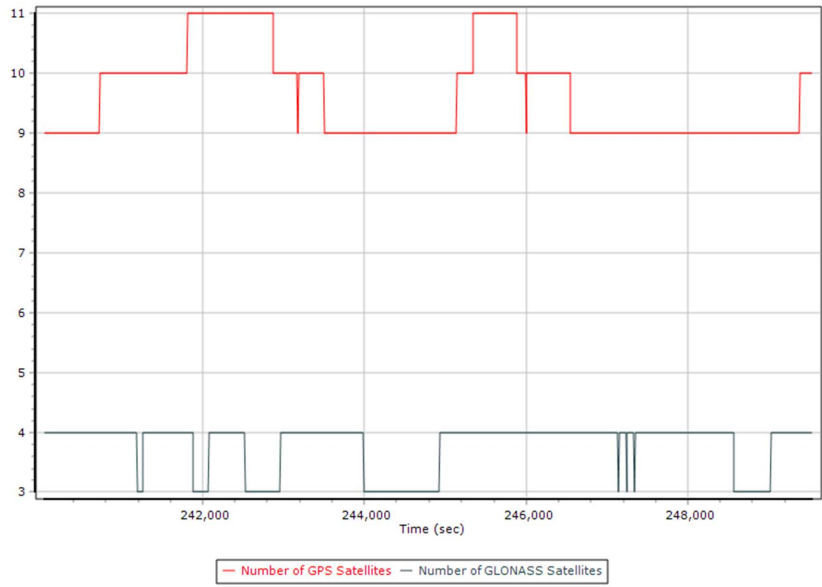
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

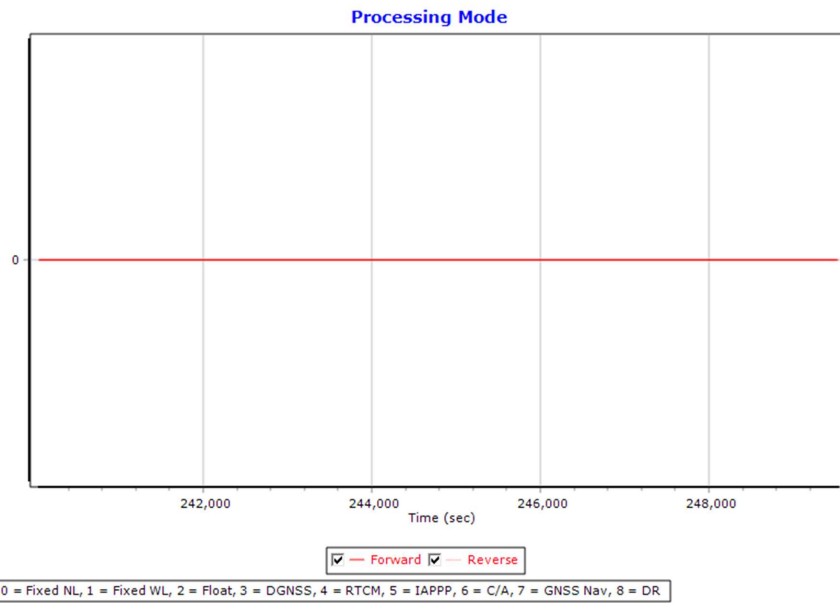
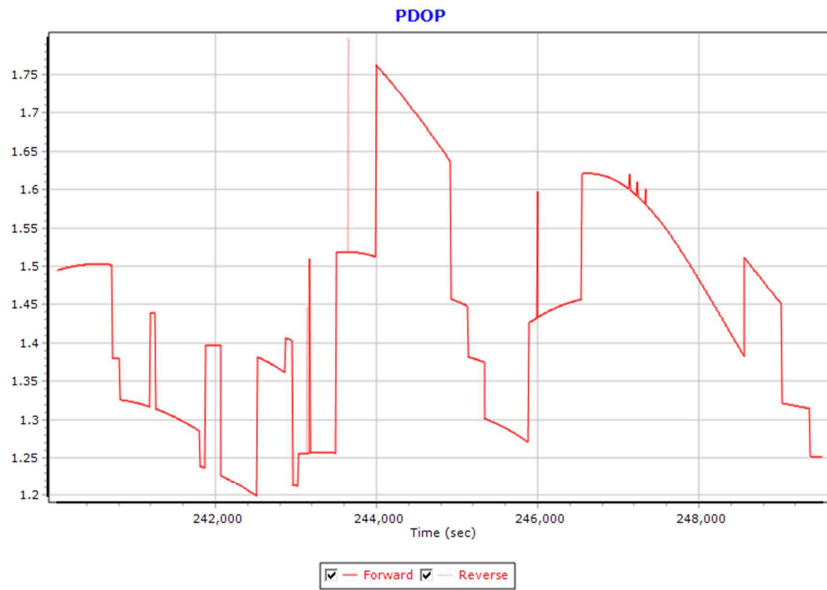
Altitude (m)

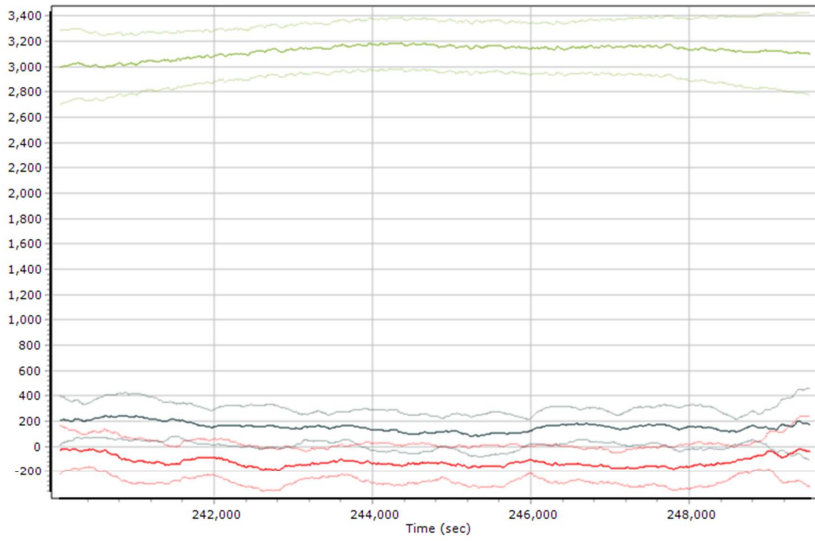




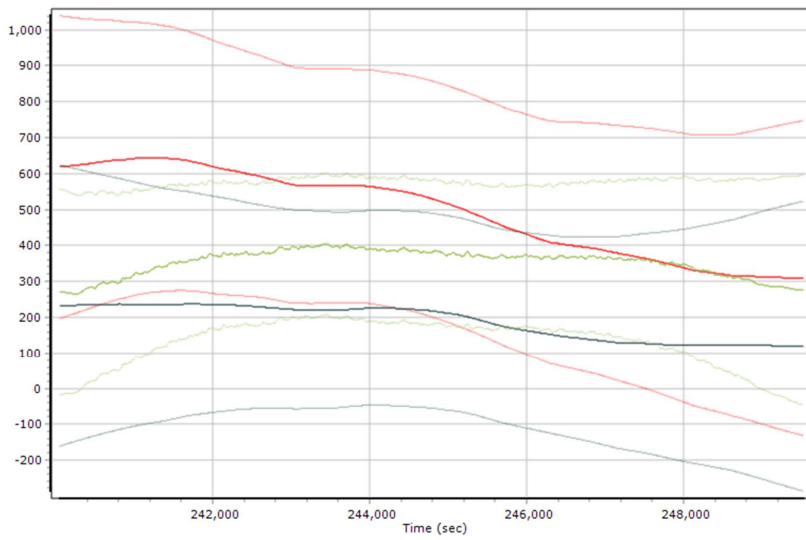




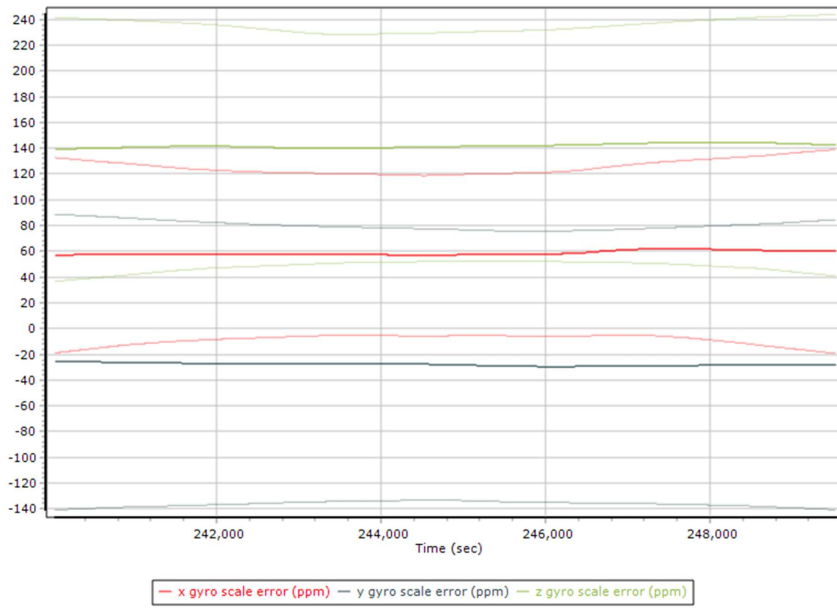
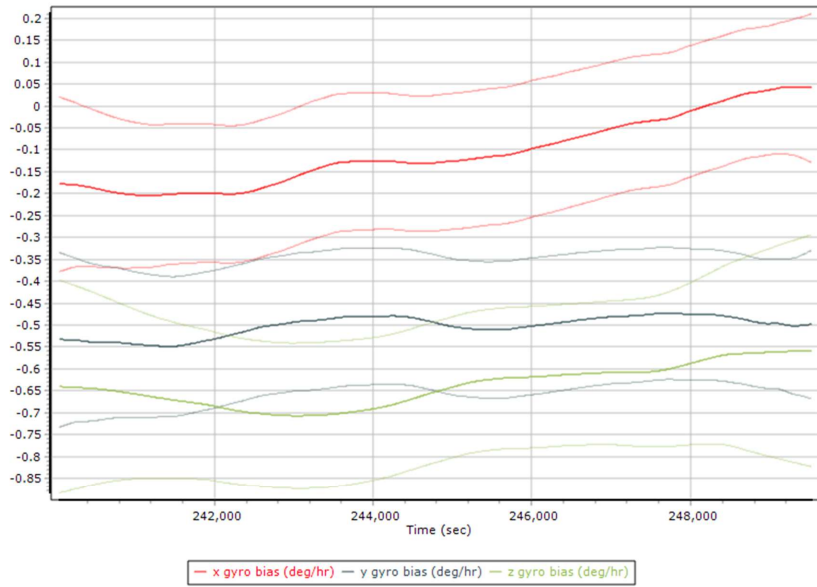




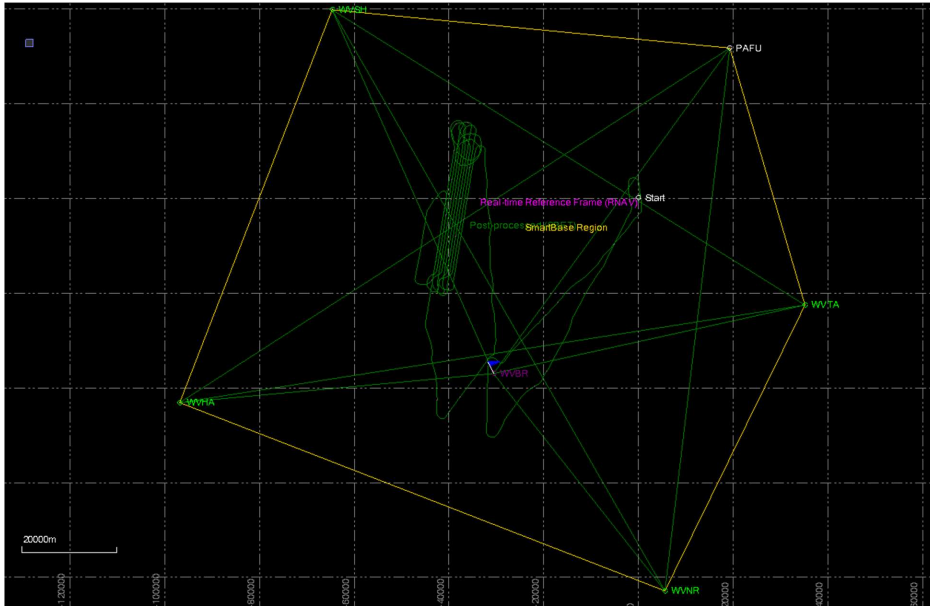
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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Reference to IMU Lever Arm

X
Y
Z

Reference to IMU Mounting Angles

X
Y
Z

Reference to Primary GNSS Lever Arm

X
Y
Z

Aircraft to Reference Mounting Angles

X
Y
Z

Standard Deviation

<3cm 10cm 50cm 1m 10m

Timing

Start 305538.000

End 322560.000

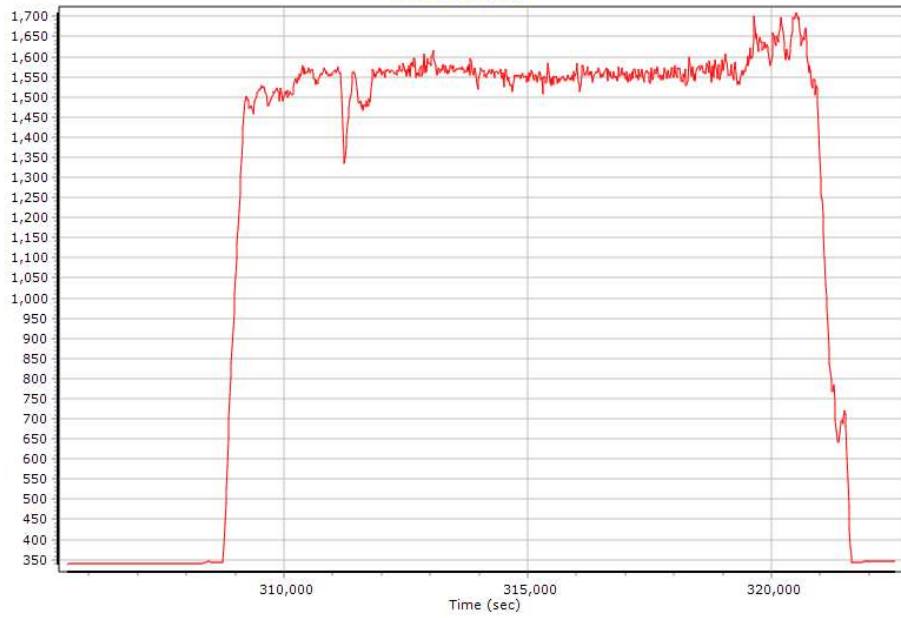
Entire time interval

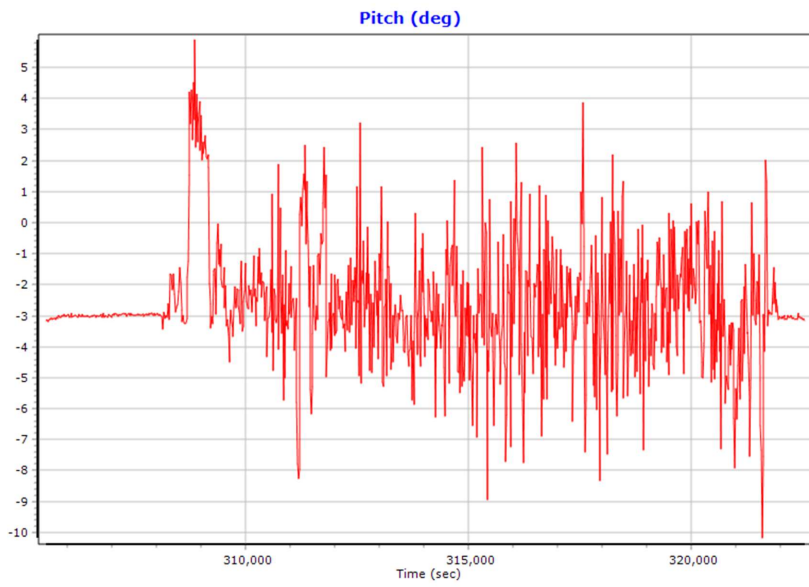
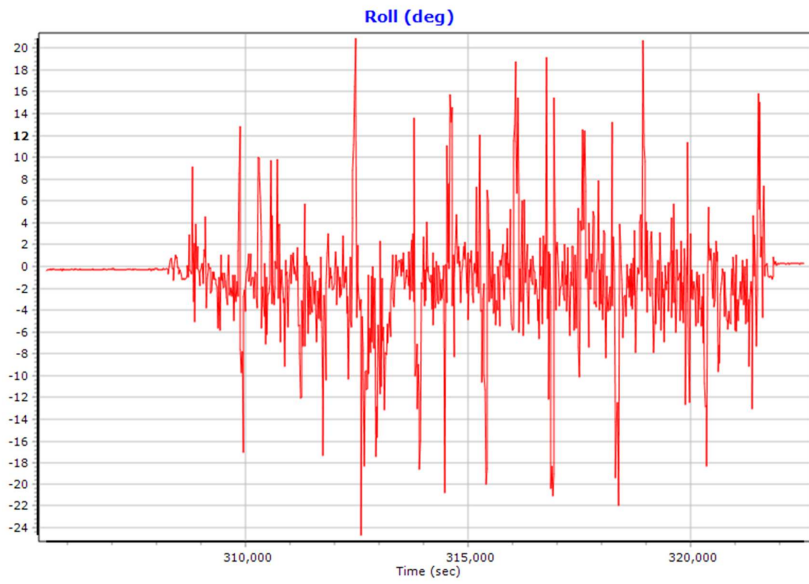
Seconds of start week

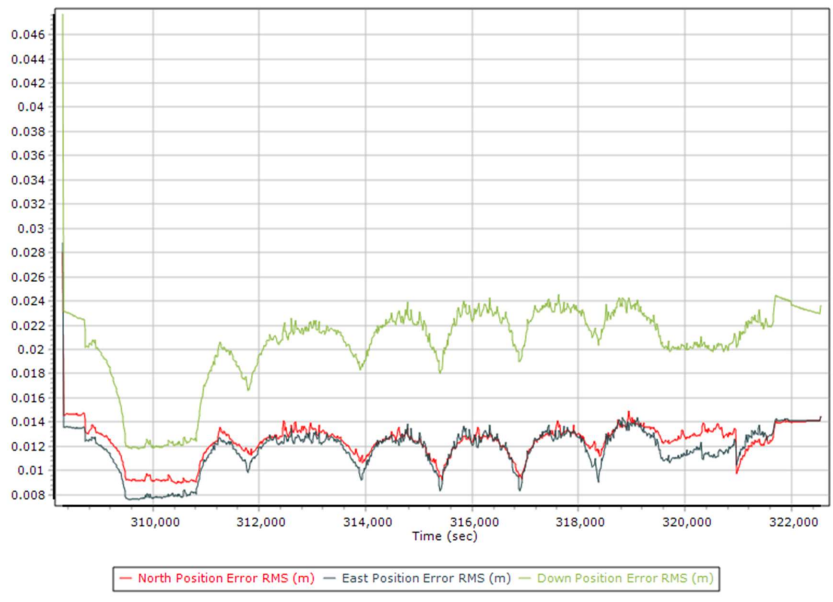
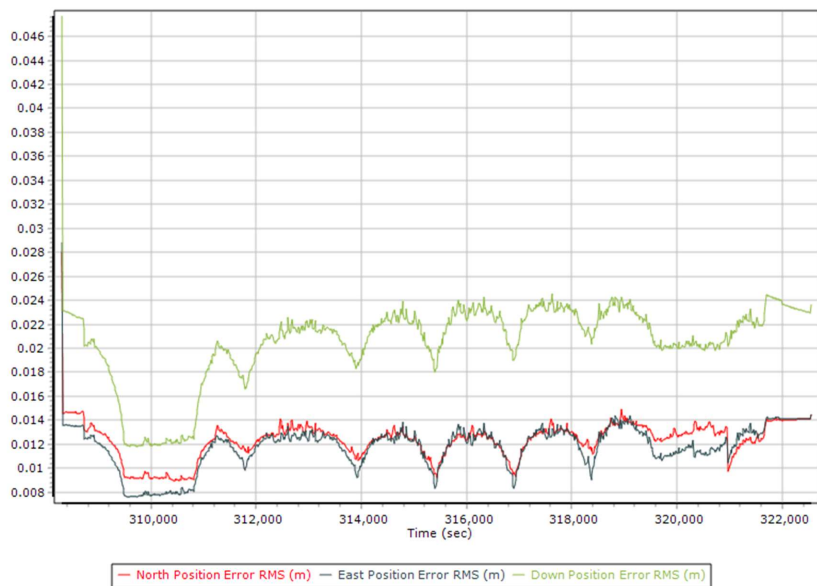
UTC Offset 18.000

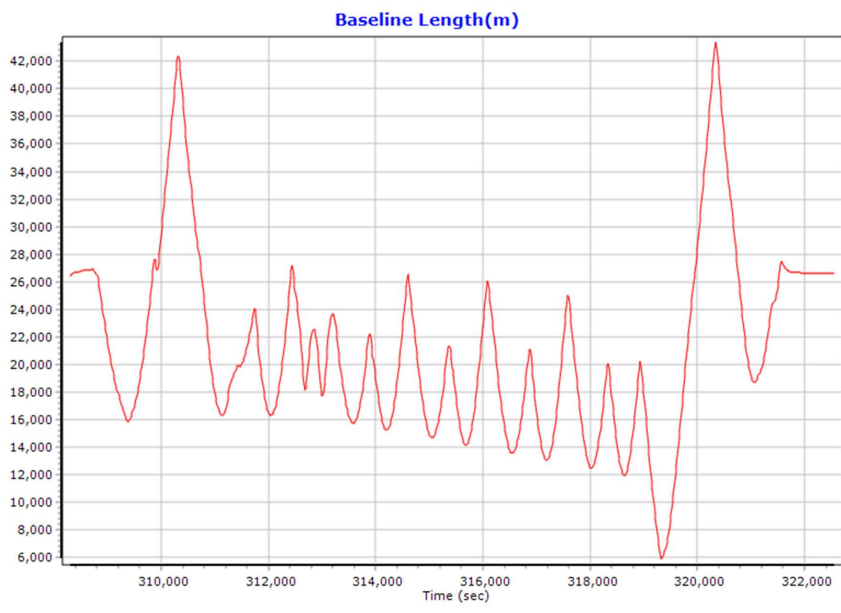
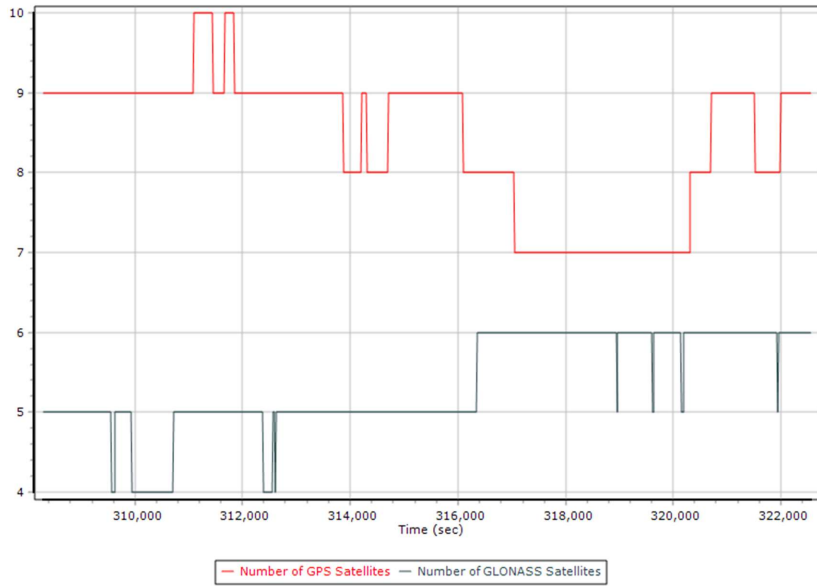
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

Altitude (m)

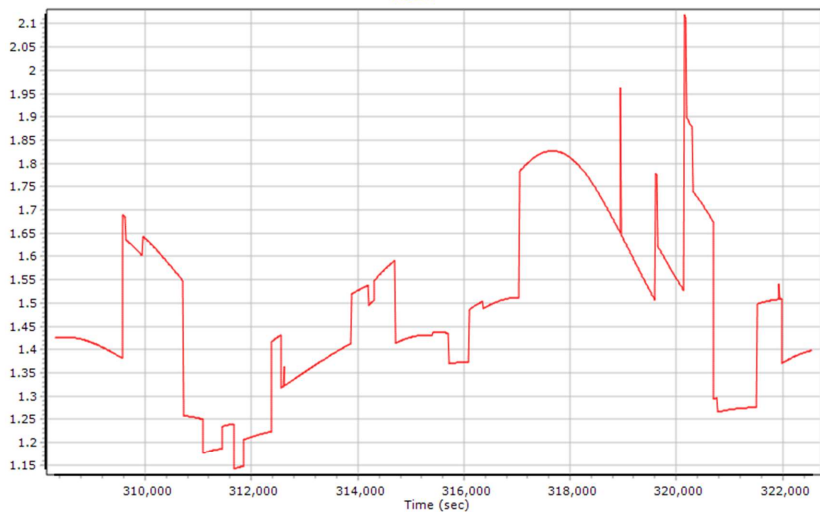






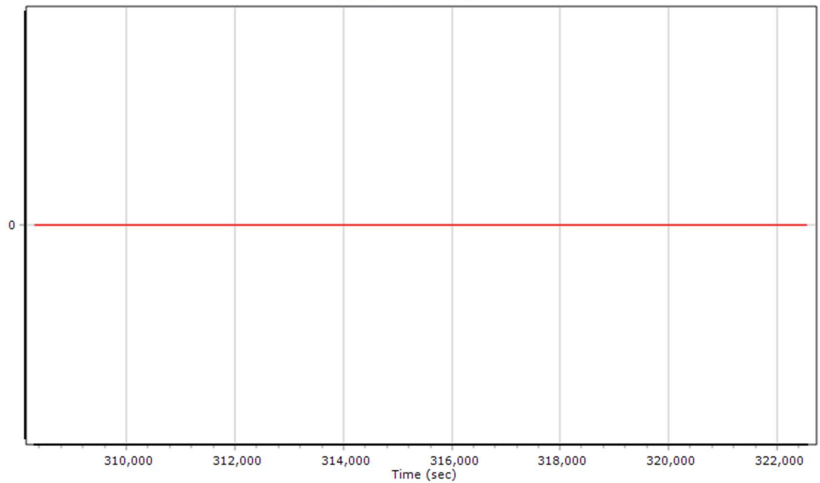


PDOP



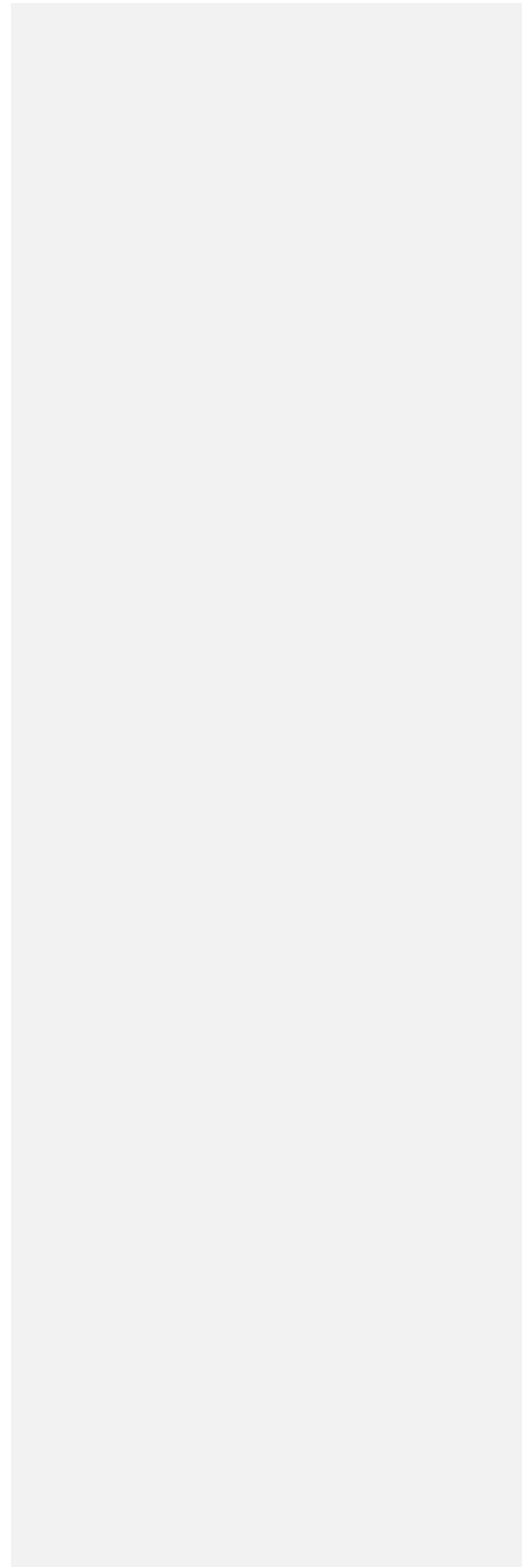
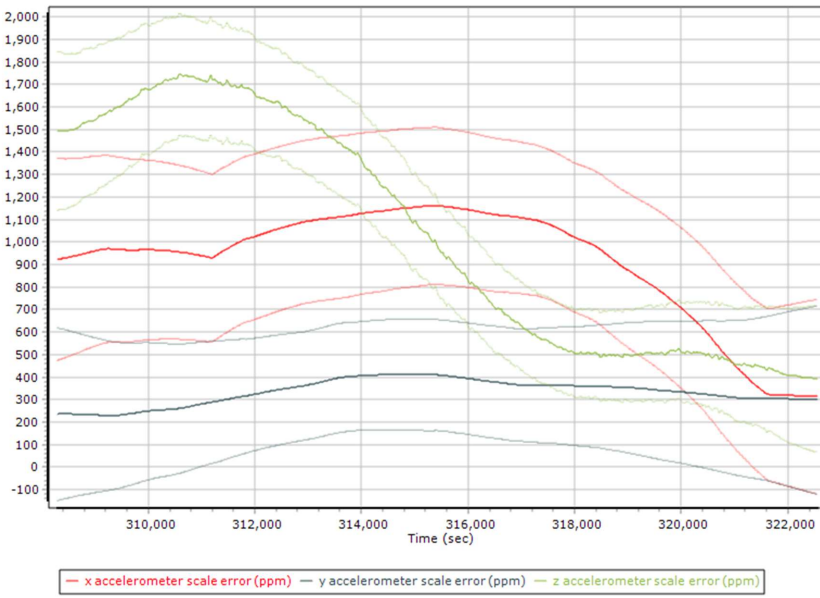
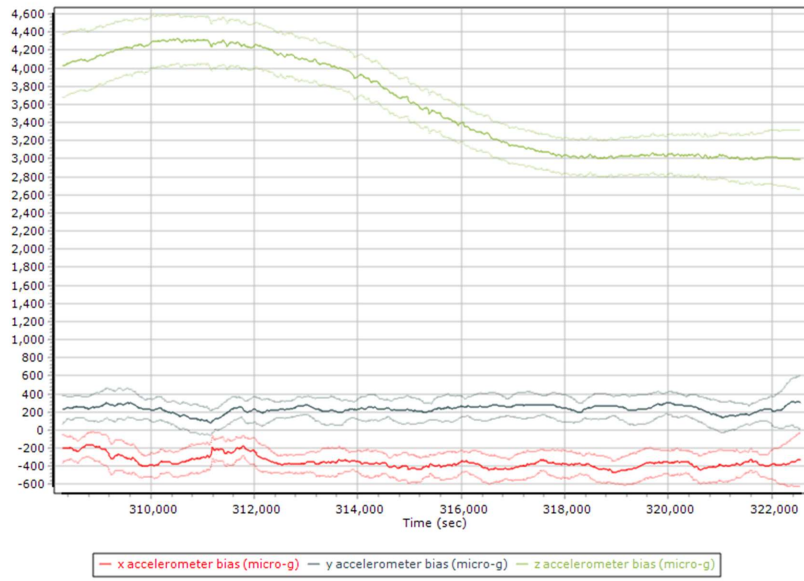
Forward Reverse

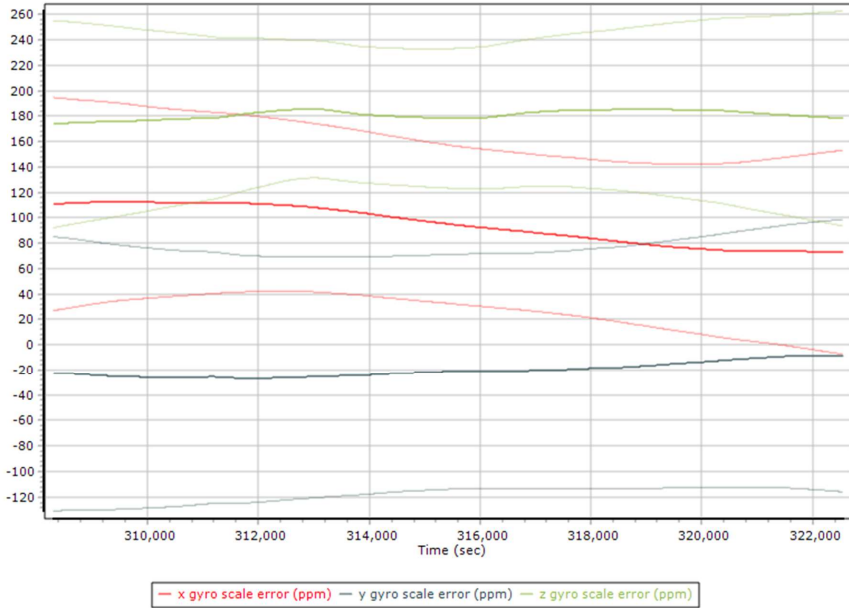
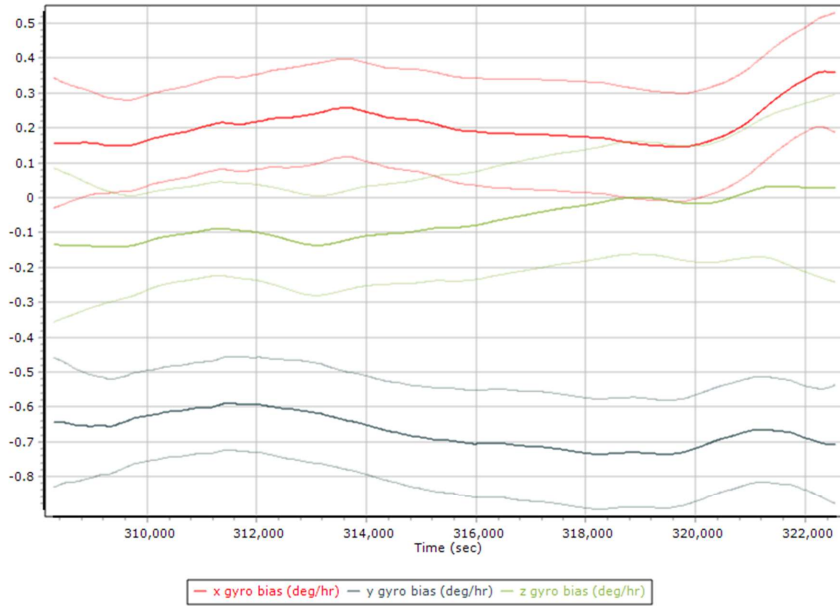
Processing Mode



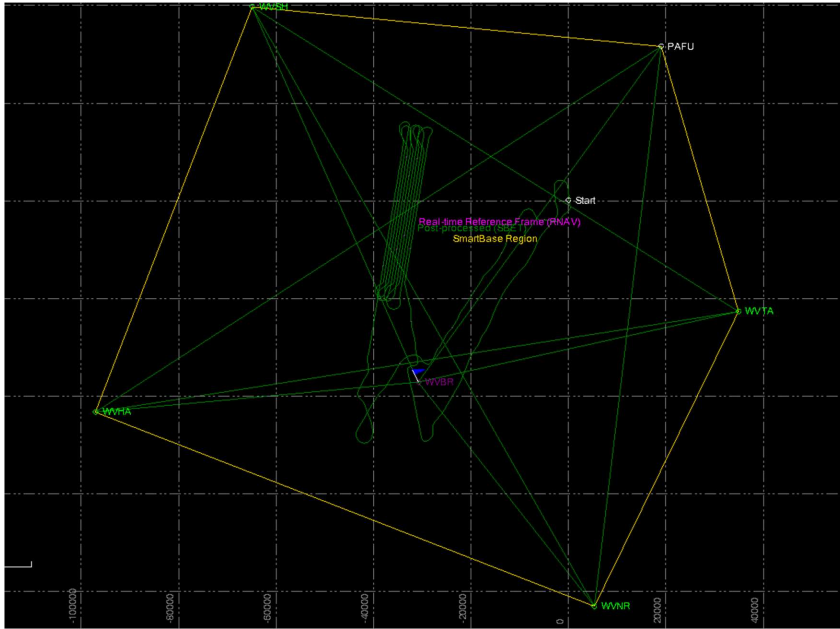
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR





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| | | | |
|--------------------------------------------|---------------------------------------|----------------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.118 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.062 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.952 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | | | |
| <input type="range" value="0.03"/> | | | |
| <p><3cm 10cm 50cm 1m 10m</p> | | | |

Timing

Start: 326364.000

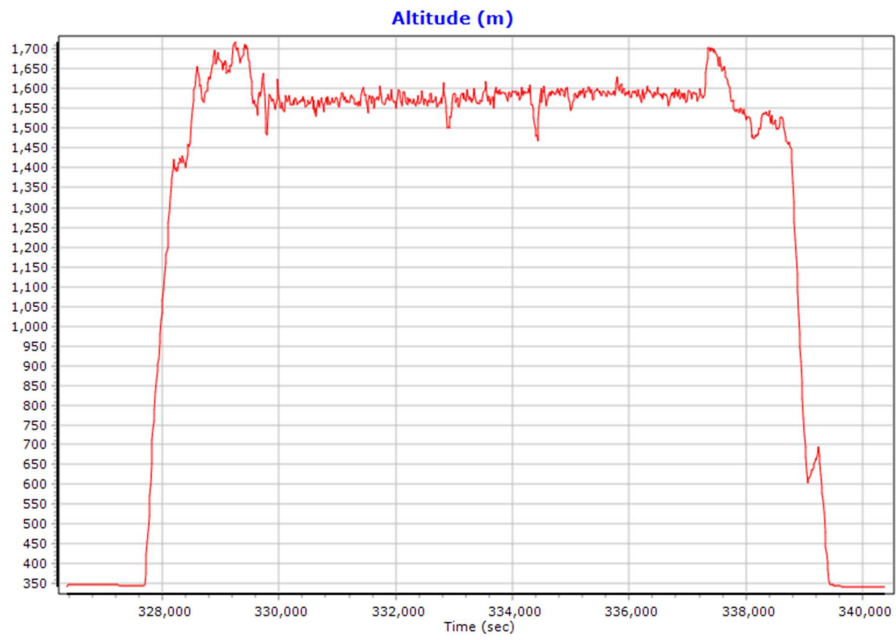
End: 340391.000

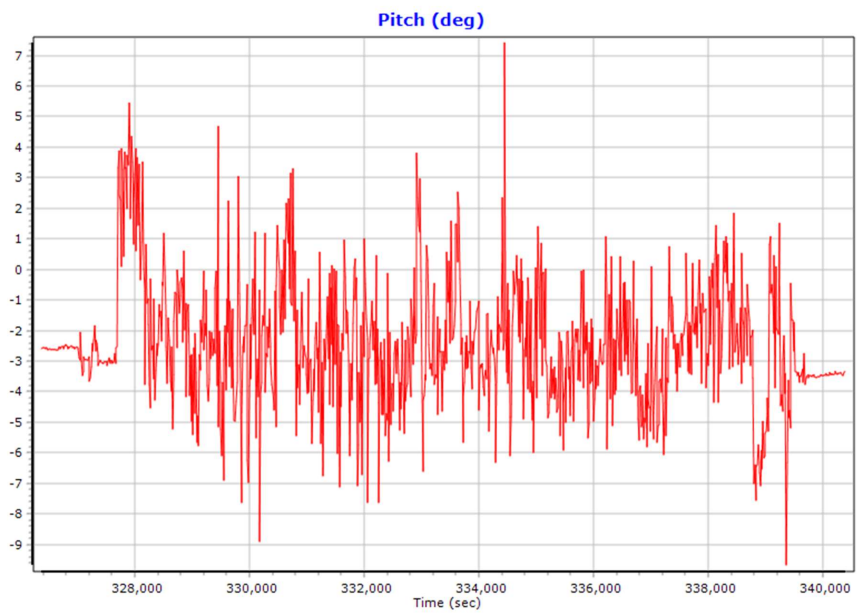
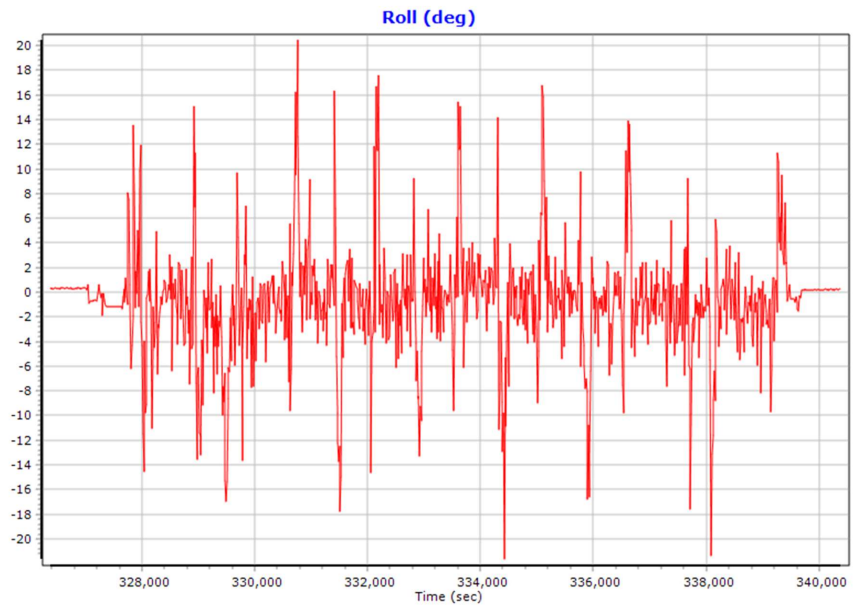
Entire time interval

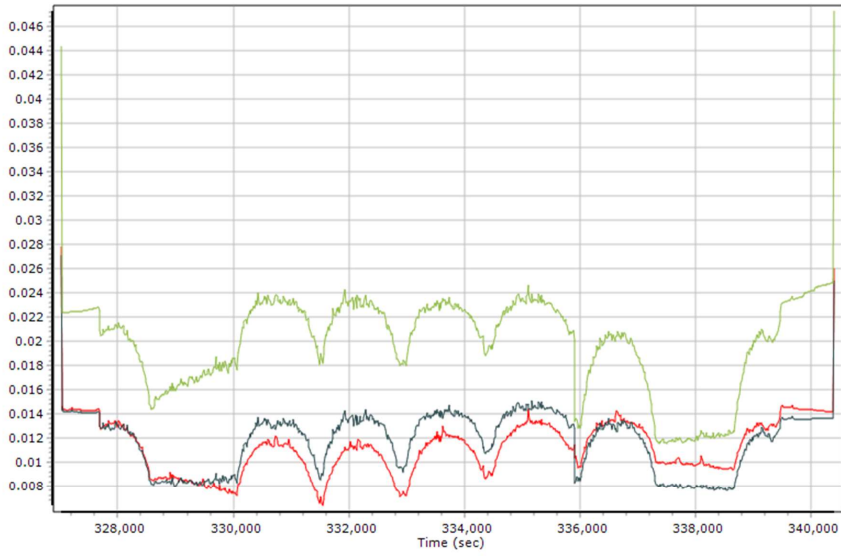
Seconds of start week

UTC Offset: 18.000

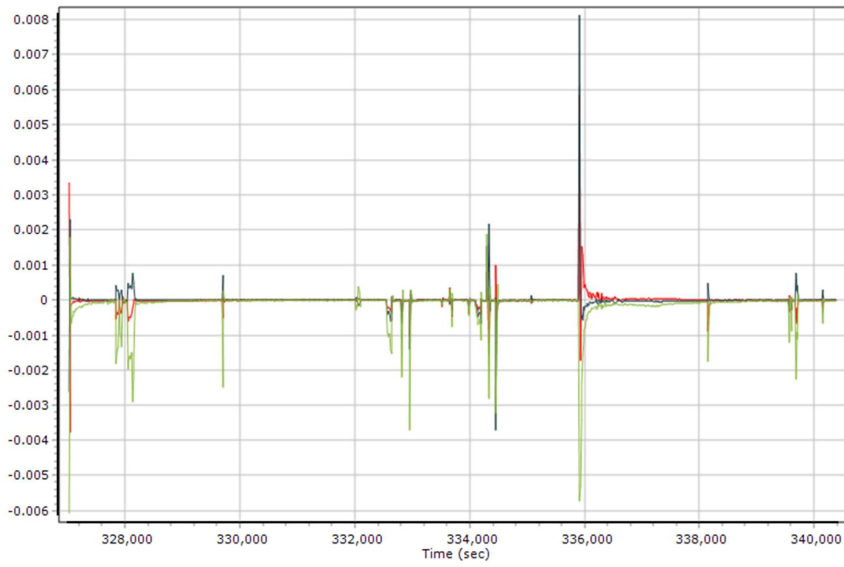
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |



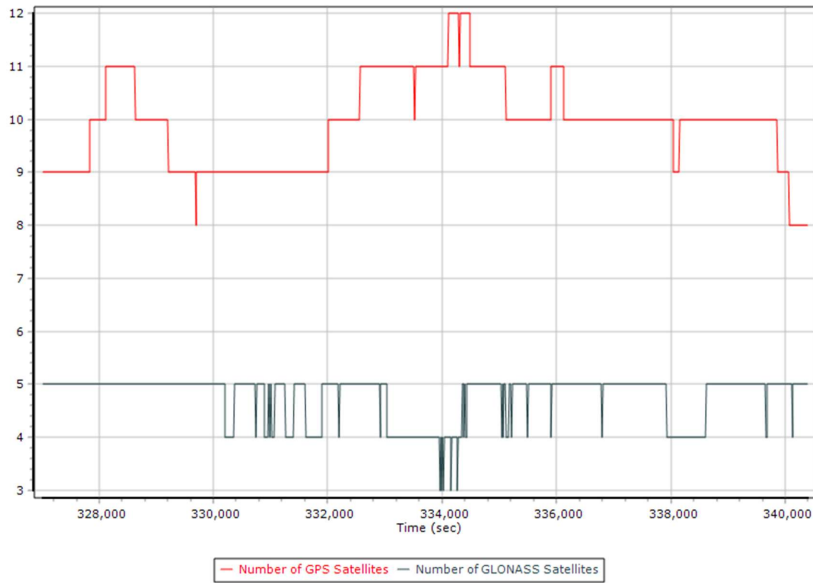




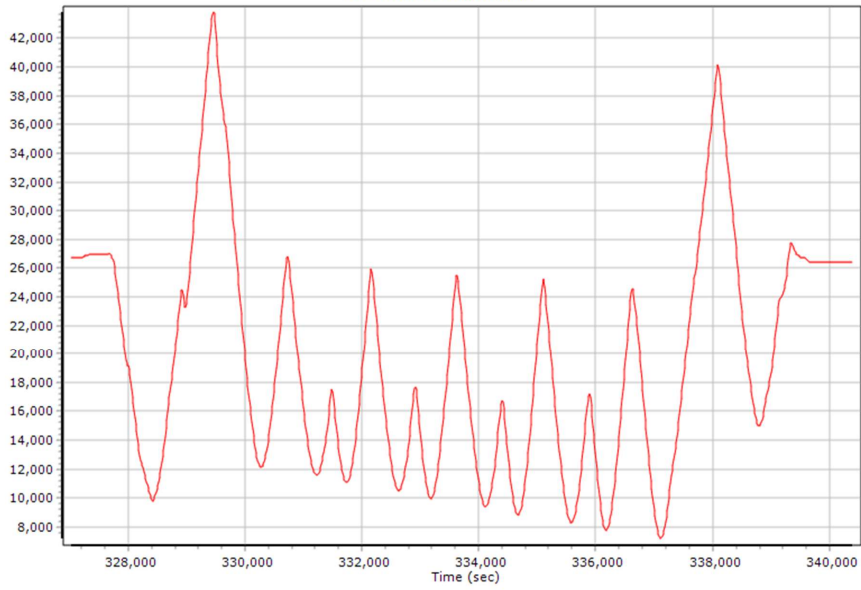
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



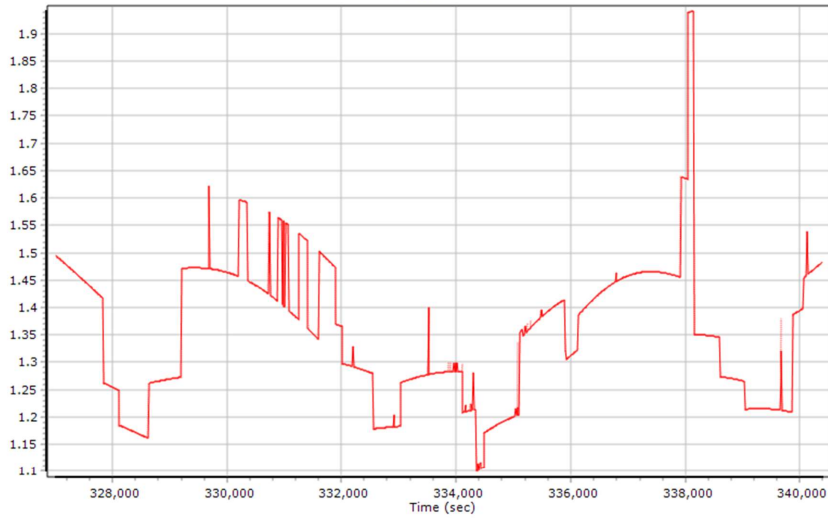
— North (m) — East (m) — Down (m) — DR mode



Baseline Length(m)

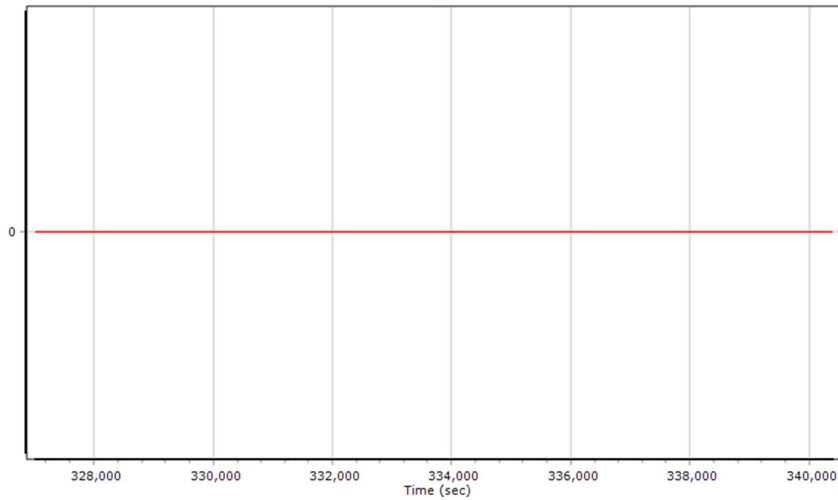


PDOP



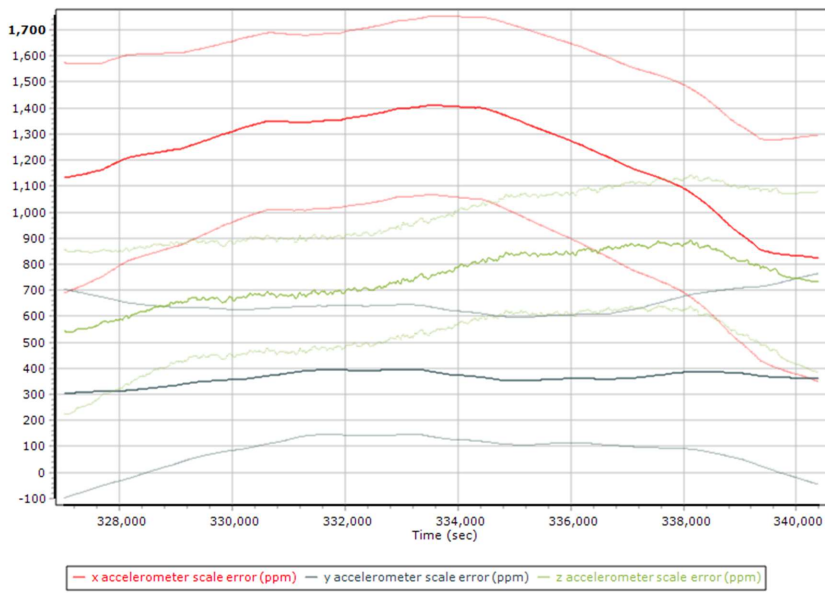
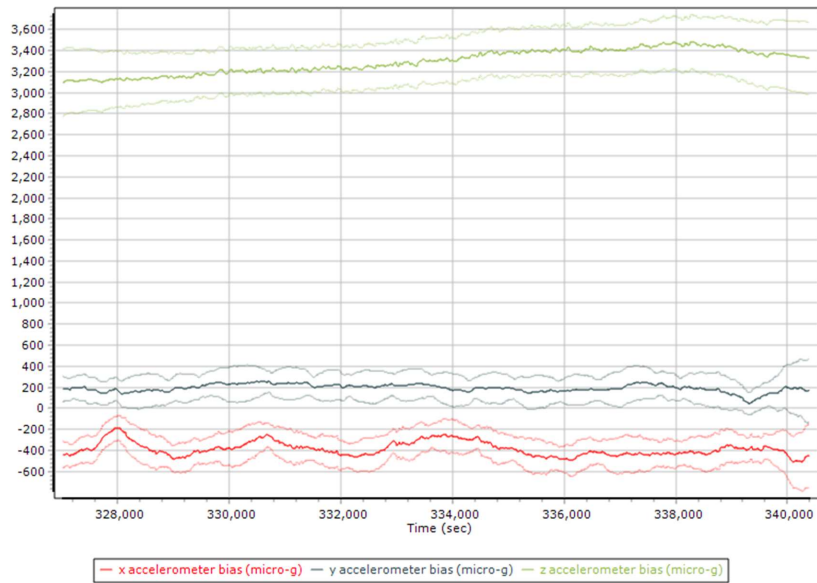
Forward Reverse

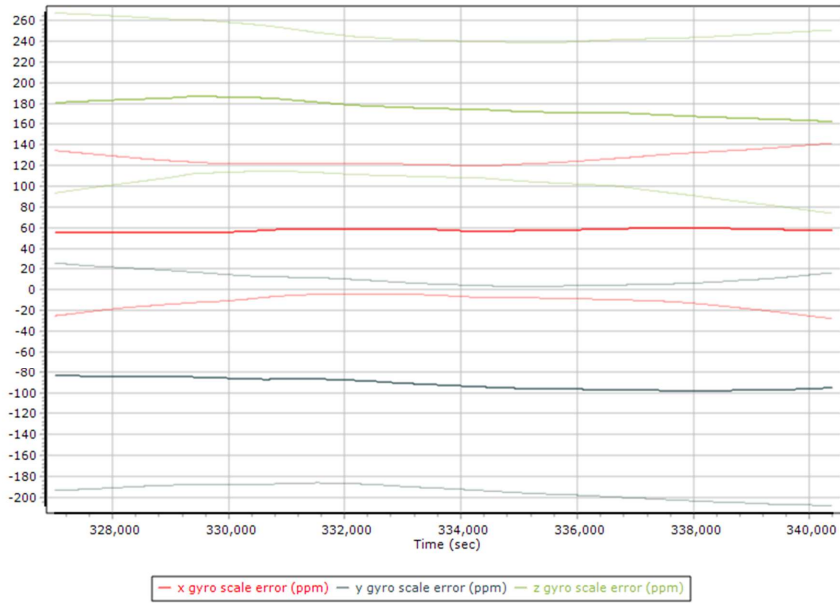
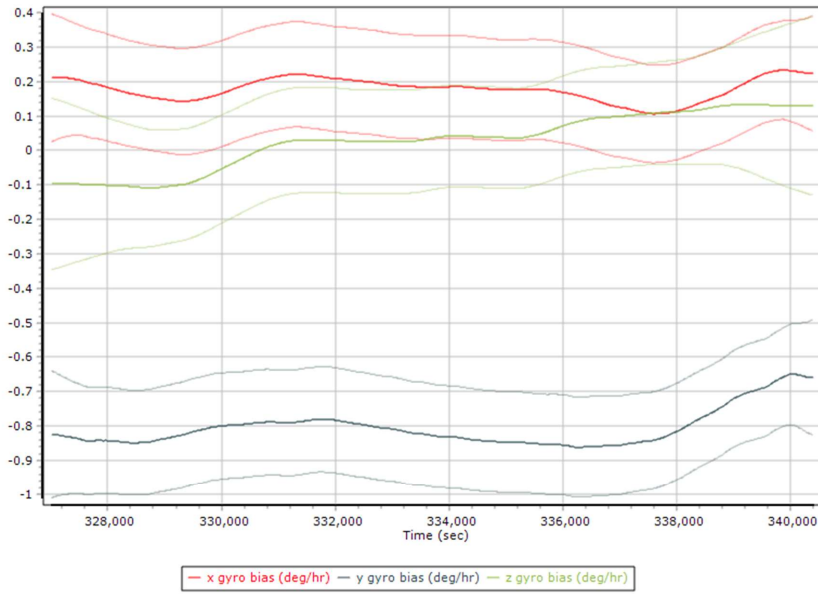
Processing Mode



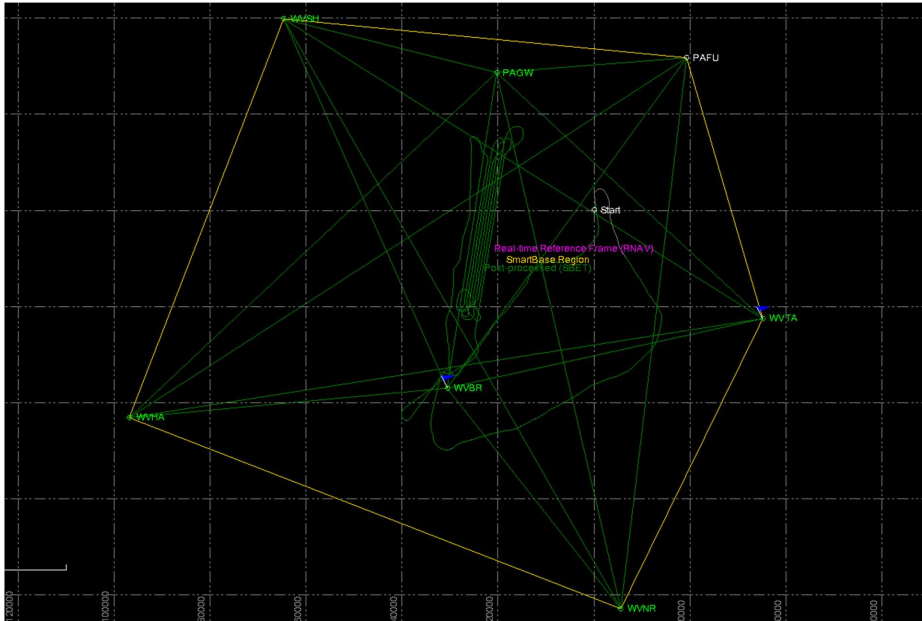
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR





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| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
|----------------------------|---------------------------------------|----------------------------------|----------------------------------------|
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |

| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
|-------------------------------------|---------------------------------------|---------------------------------------|----------------------------------------|
| X | <input type="text" value="-0.118 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.062 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.952 m"/> | Z | <input type="text" value="0.000 deg"/> |

Standard Deviation
 <3cm 10cm 50cm 1m 10m

Timing

Start 390213.000

End 403386.609

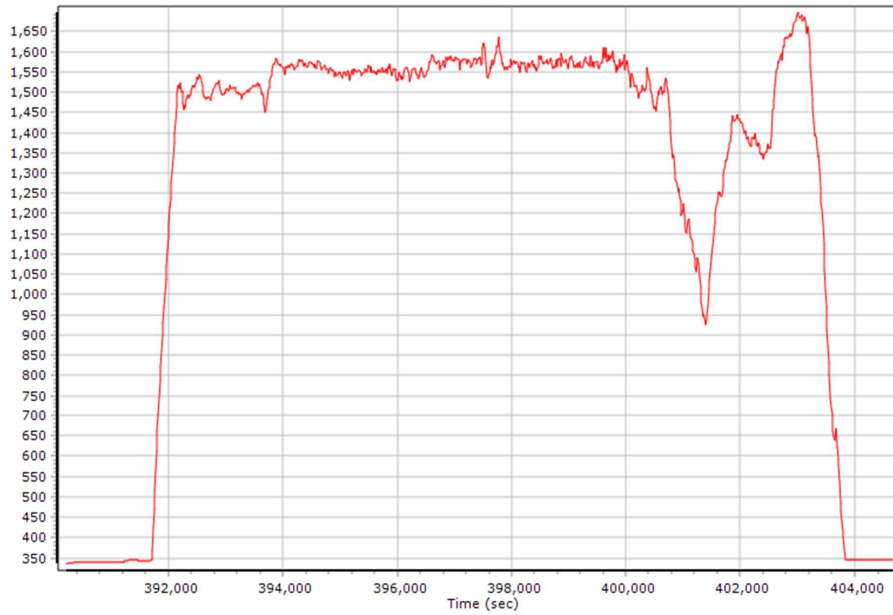
Entire time interval

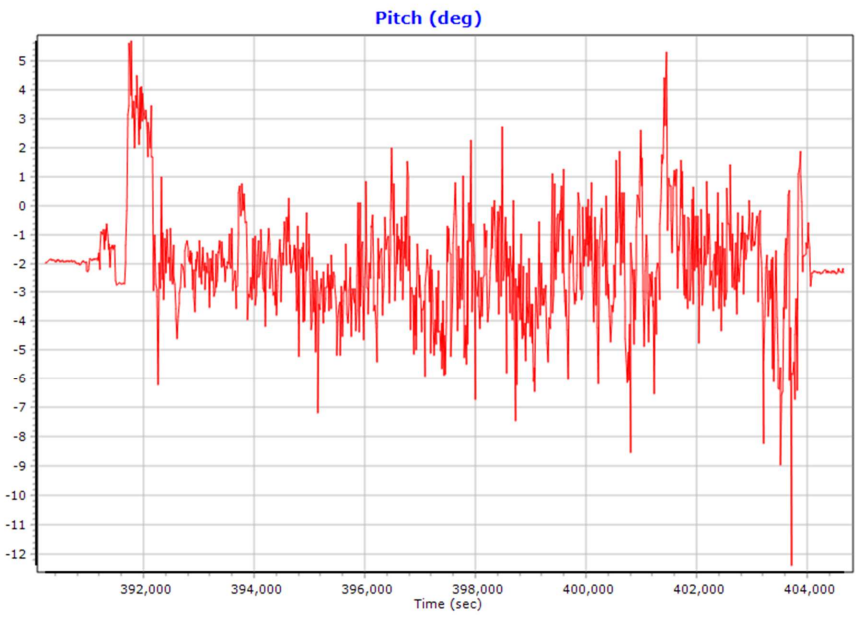
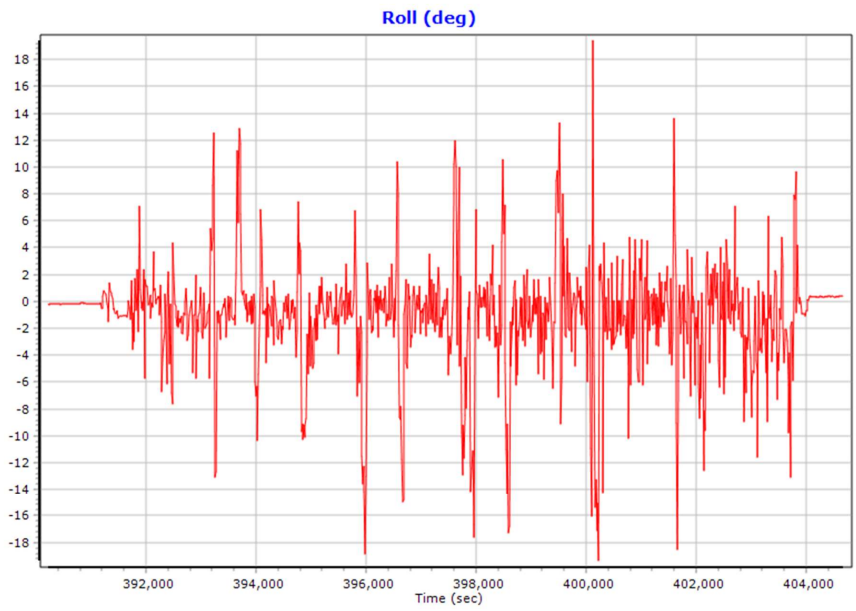
Seconds of start week

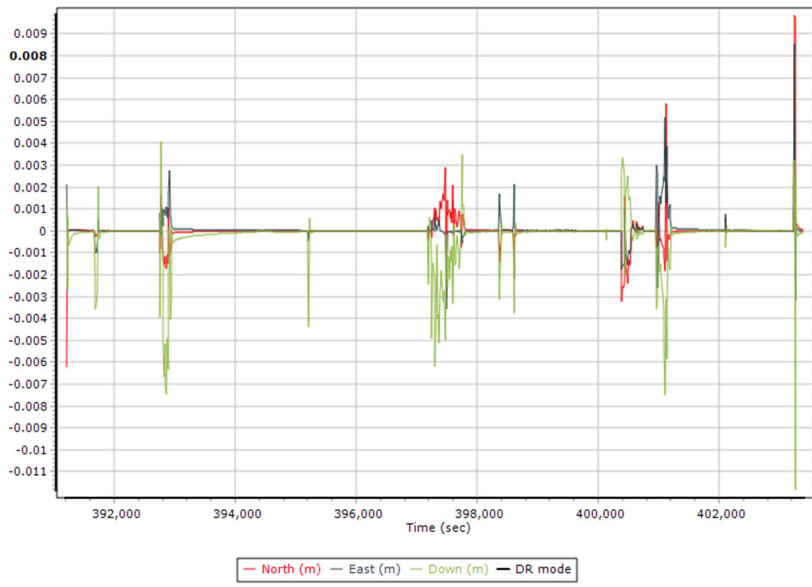
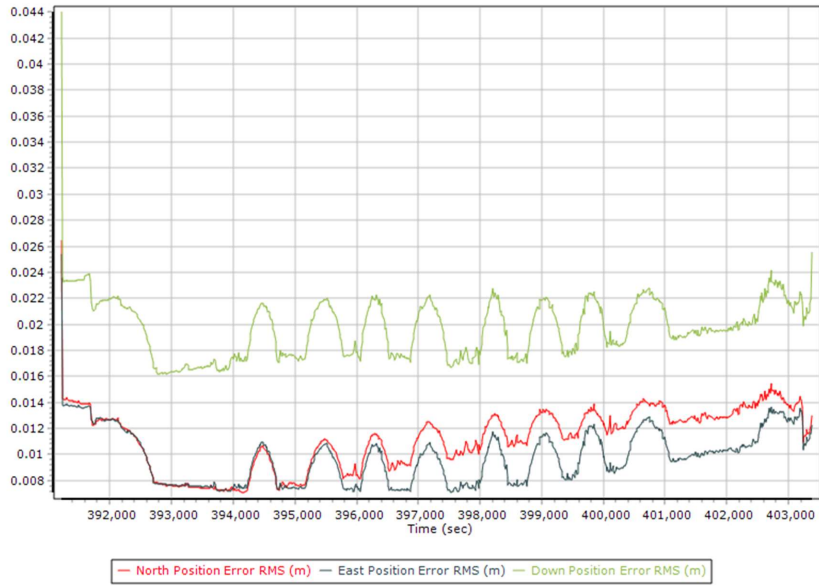
UTC Offset 18.000

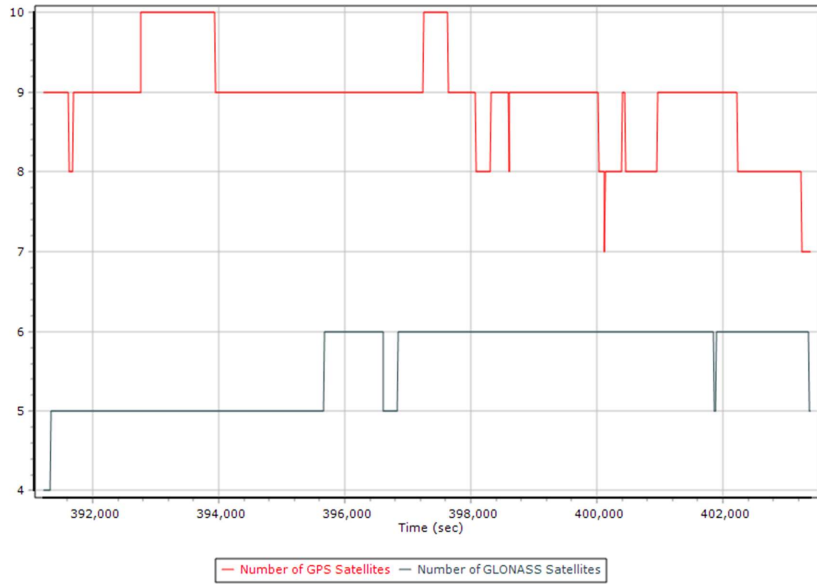
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

Altitude (m)

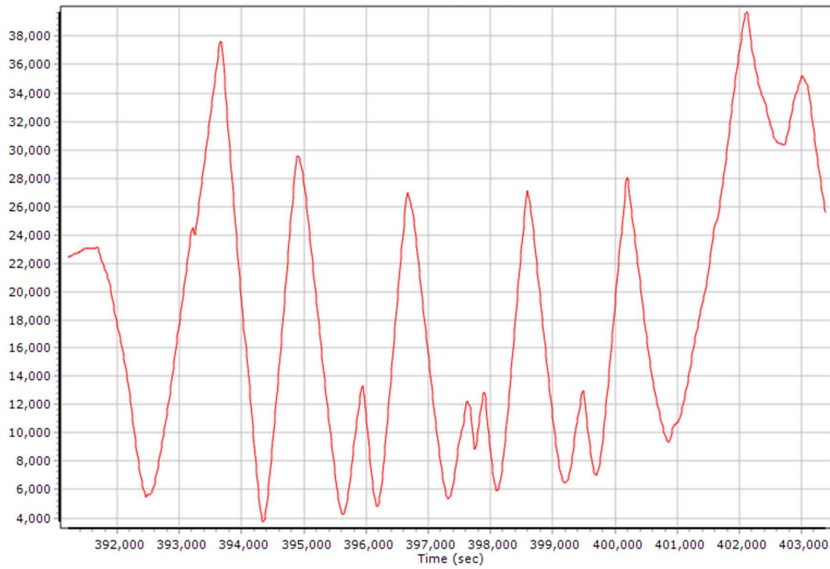




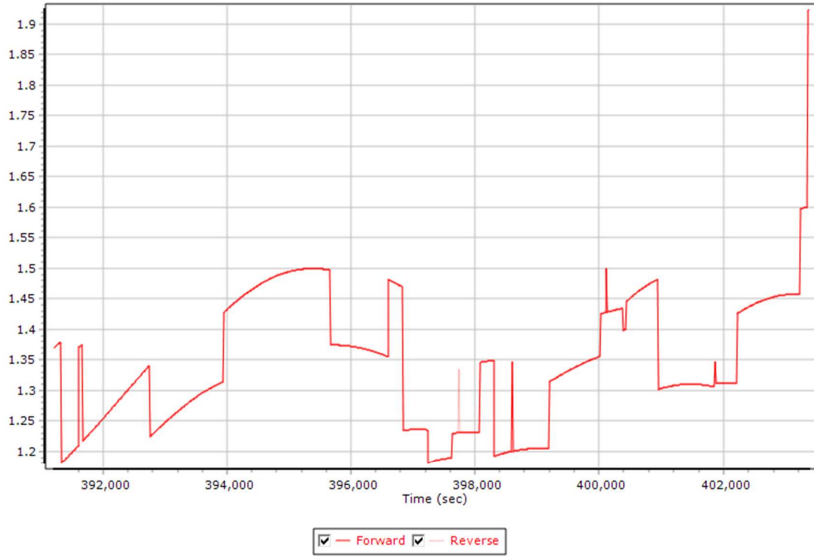




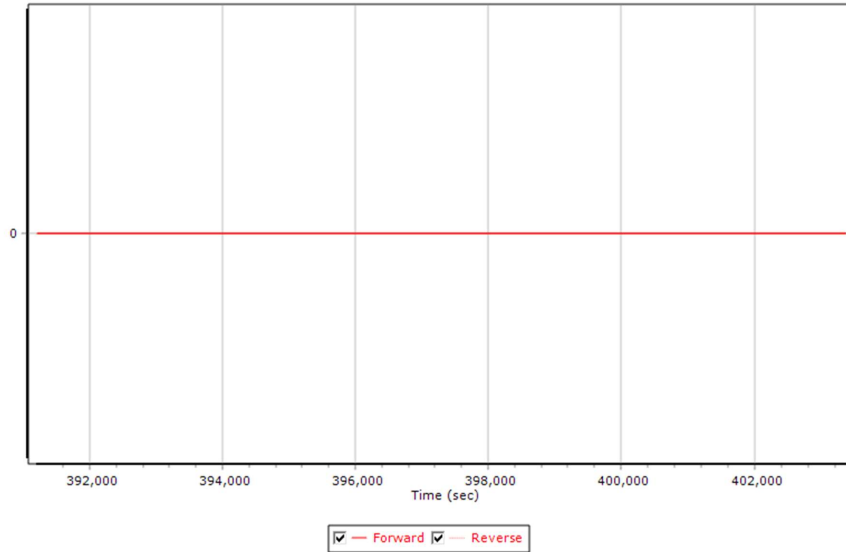
Baseline Length(m)



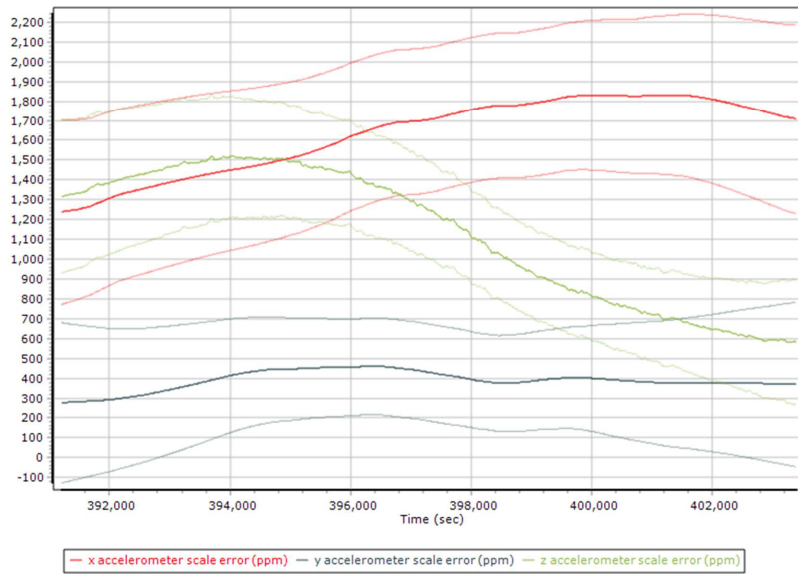
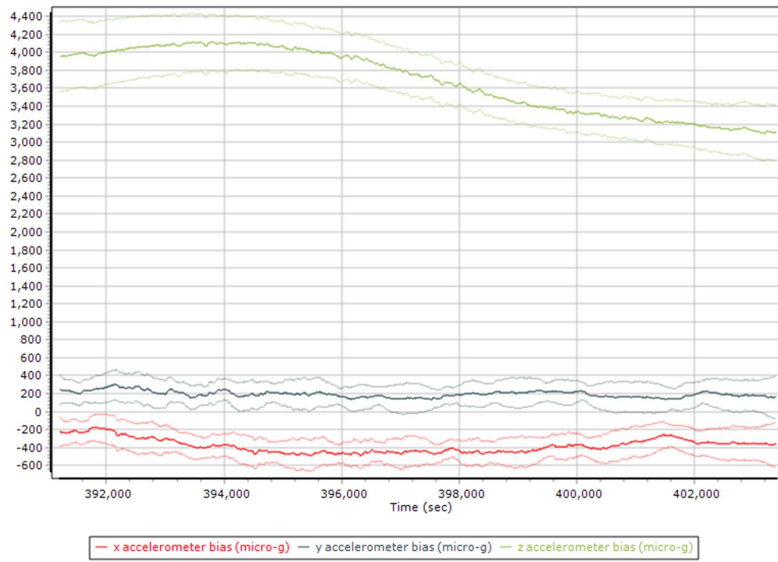
PDOP

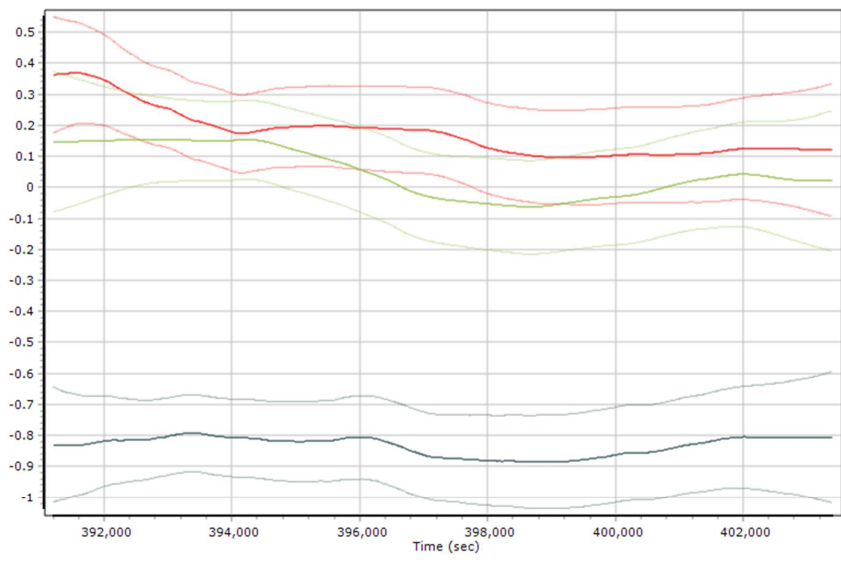


Processing Mode

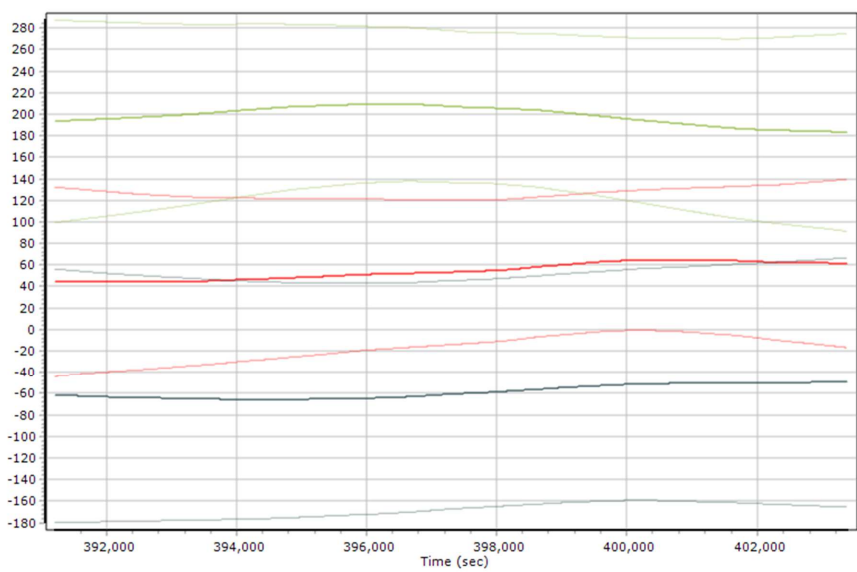


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



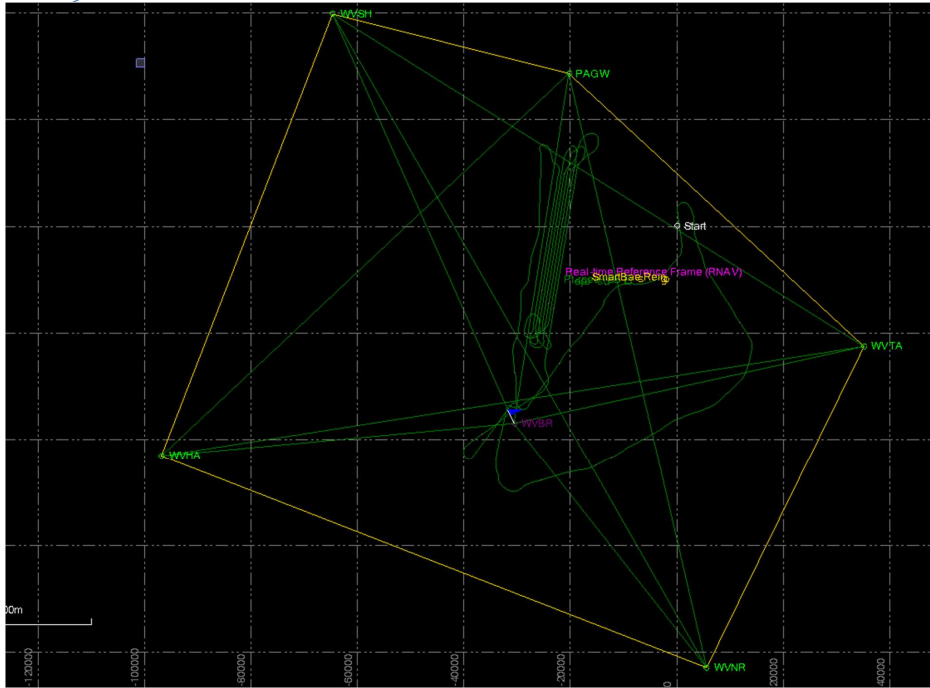


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



— x gyro scale error (ppm) — y gyro scale error (ppm) — z gyro scale error (ppm)

UNB19108A



Reference to IMU Lever Arm

| | |
|---|---------------------------------------|
| X | <input type="text" value="0.034 m"/> |
| Y | <input type="text" value="0.018 m"/> |
| Z | <input type="text" value="-0.155 m"/> |

Reference to IMU Mounting Angles

| | |
|---|----------------------------------------|
| X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="0.000 deg"/> |

Reference to Primary GNSS Lever Arm

| | |
|---|---------------------------------------|
| X | <input type="text" value="-0.118 m"/> |
| Y | <input type="text" value="-0.062 m"/> |
| Z | <input type="text" value="-0.952 m"/> |

Standard Deviation

<3cm 10cm 50cm 1m 10m

Aircraft to Reference Mounting Angles

| | |
|---|----------------------------------------|
| X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="0.000 deg"/> |

Timing

Start:

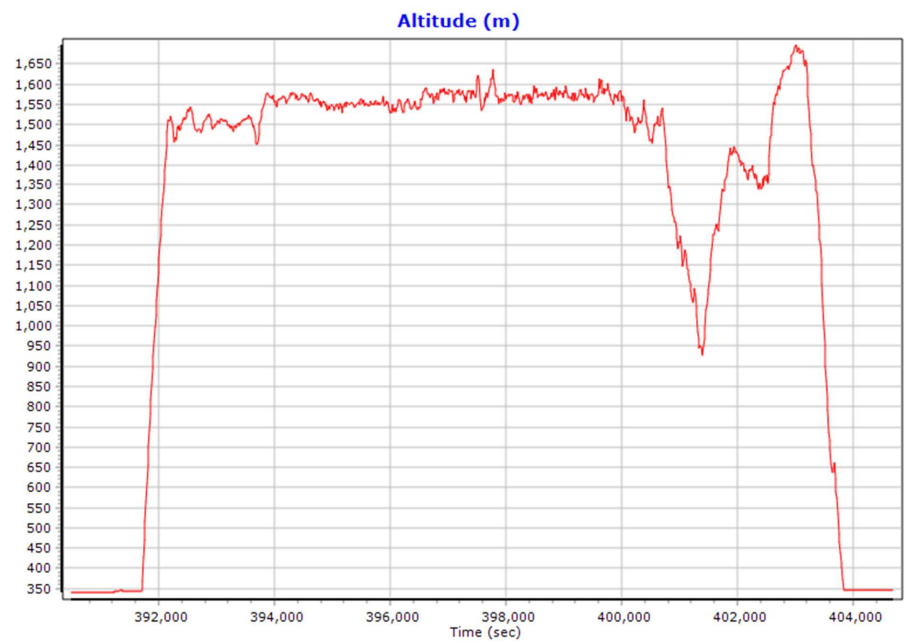
End:

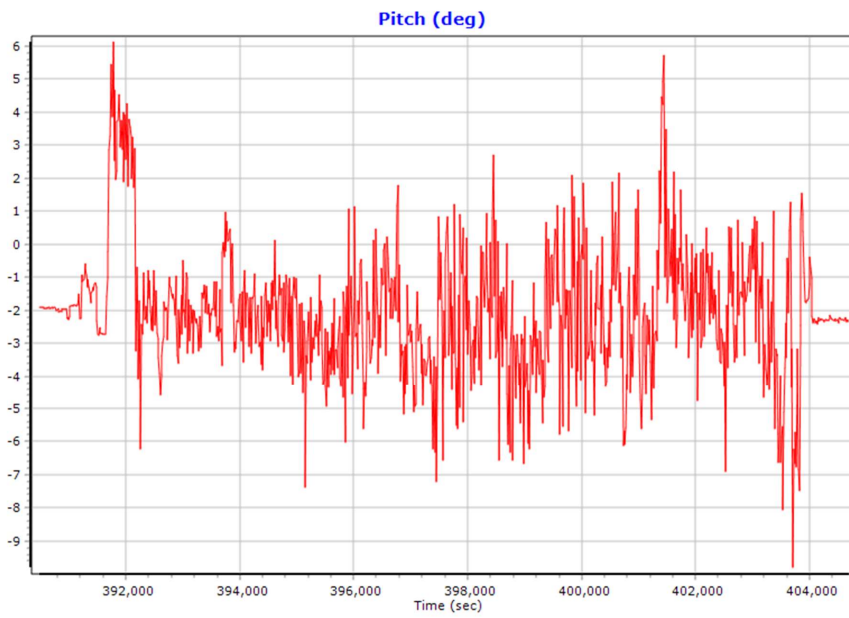
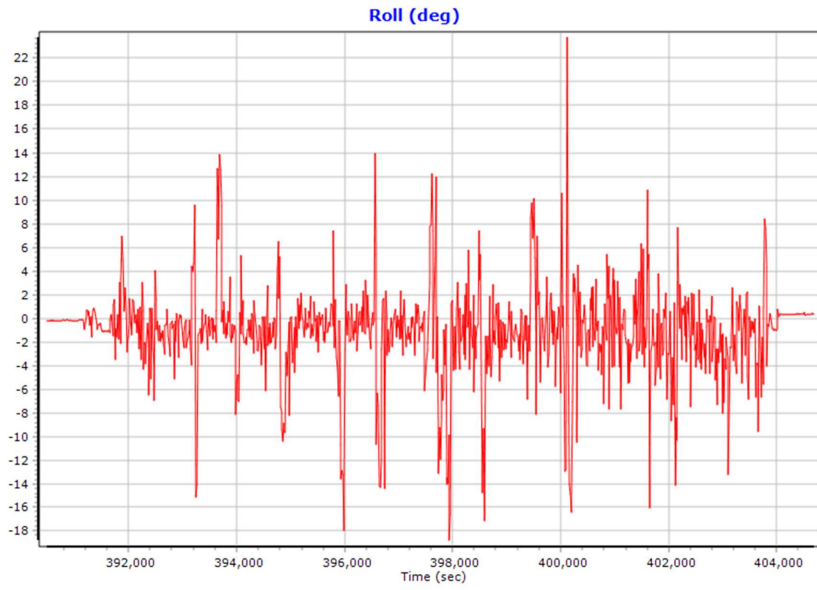
Entire time interval

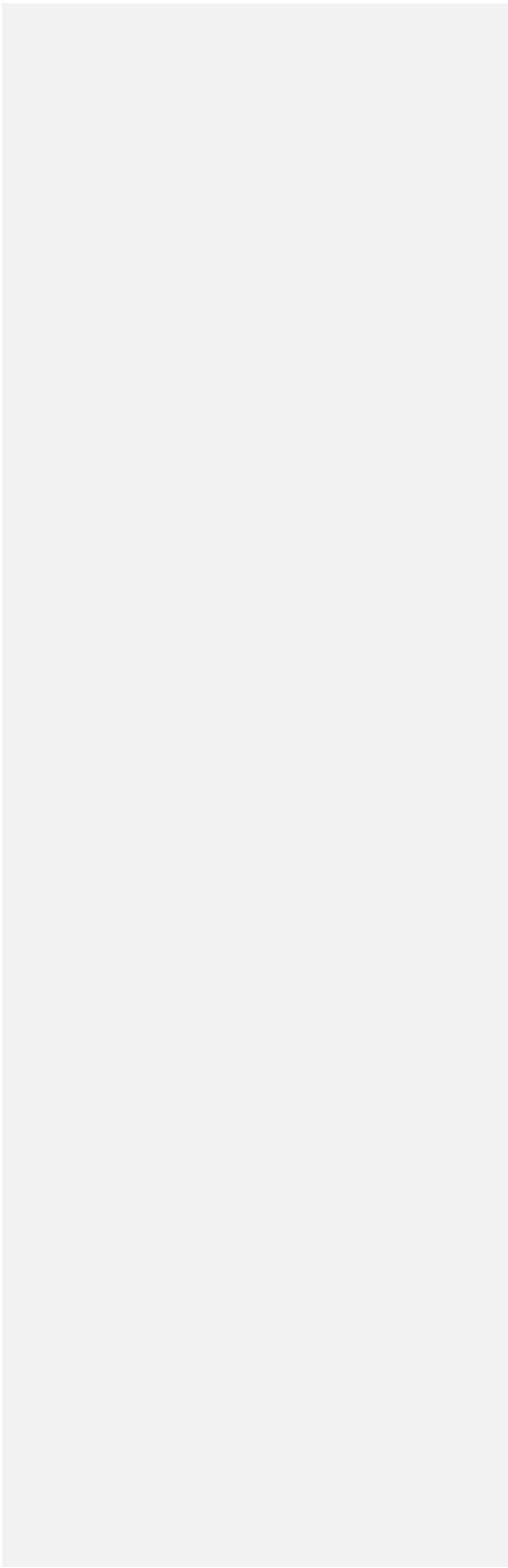
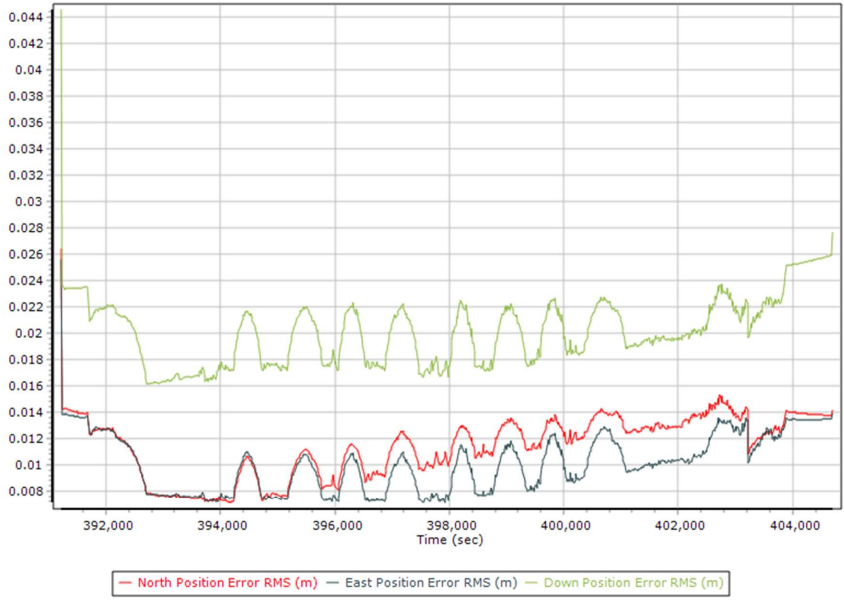
Seconds of start week

UTC Offset:

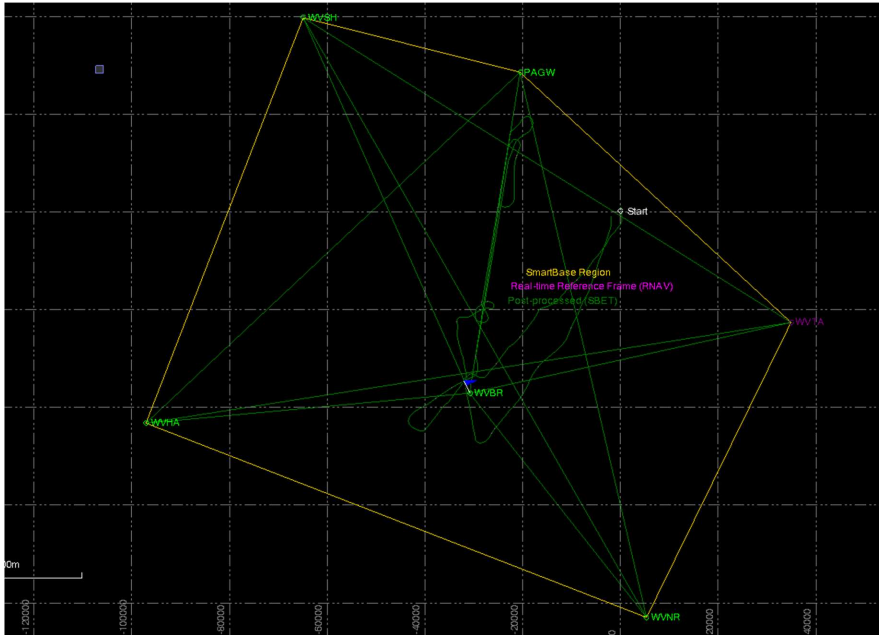
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |







UNB19108B



| | | | |
|--------------------------------------------|---------------------------------------|----------------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.118 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.062 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.952 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | | | |
| <input type="range" value="0.03"/> | | | |
| <p><3cm 10cm 50cm 1m 10m</p> | | | |

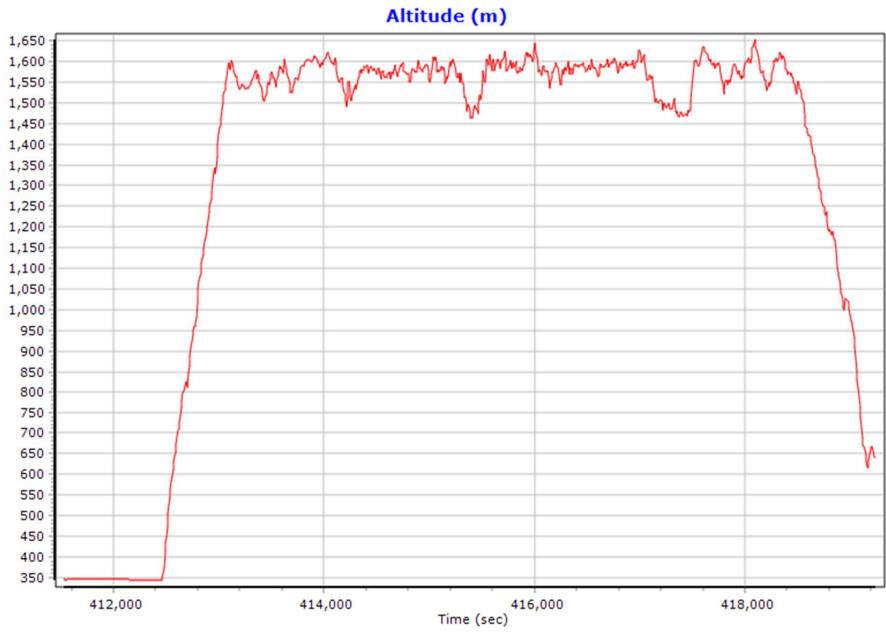
Timing

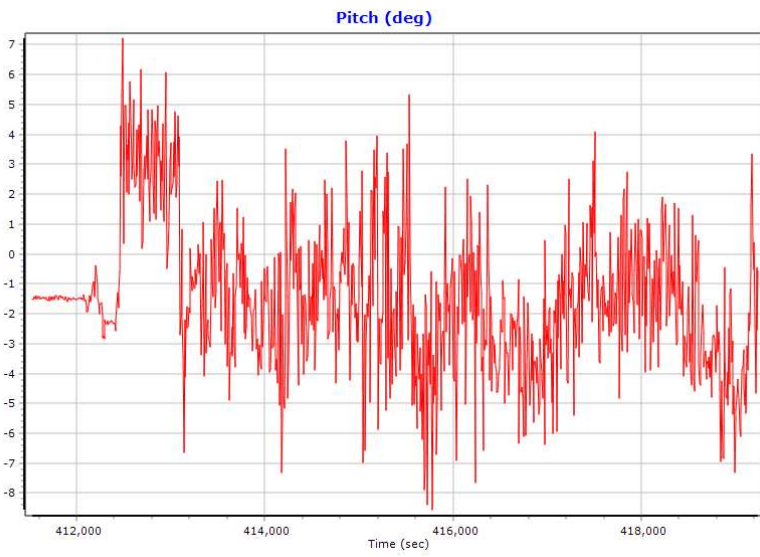
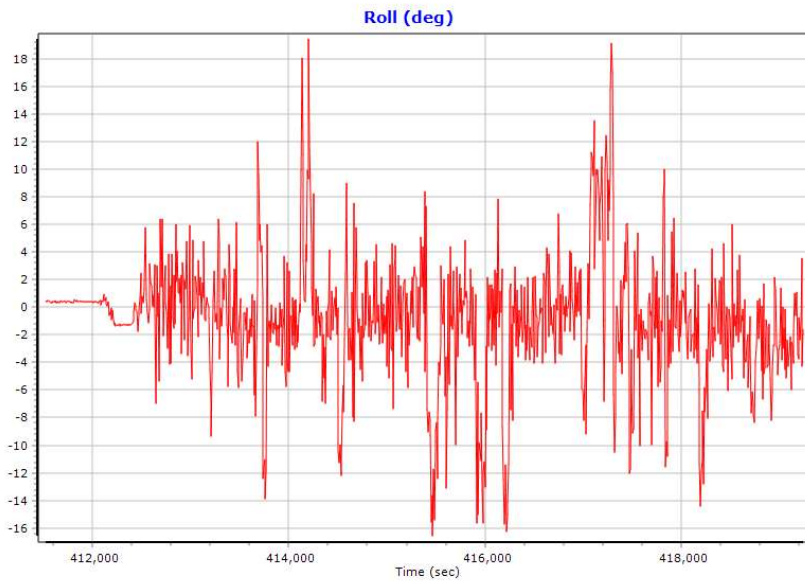
Start: 411529.000
 End: 419243.000

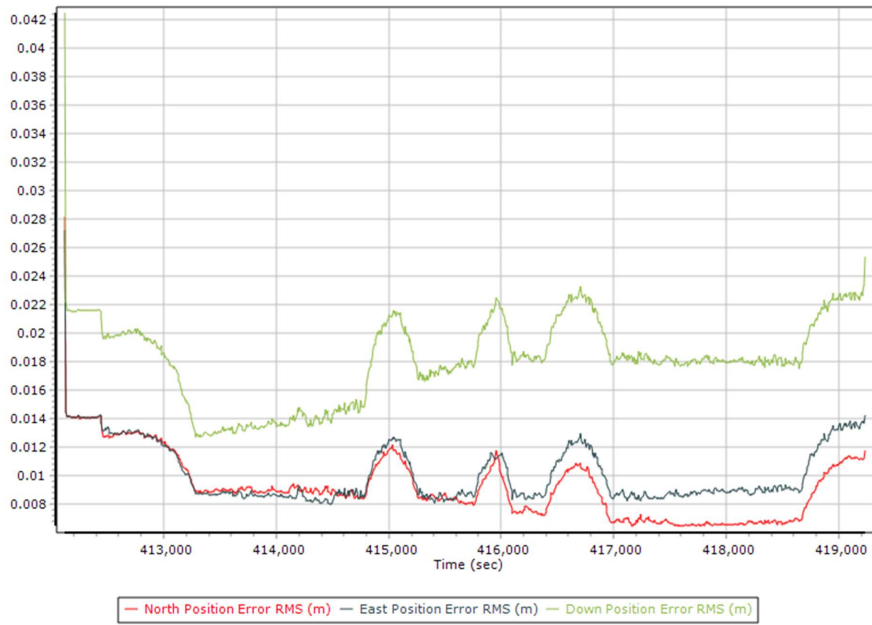
Entire time interval
 Seconds of start week

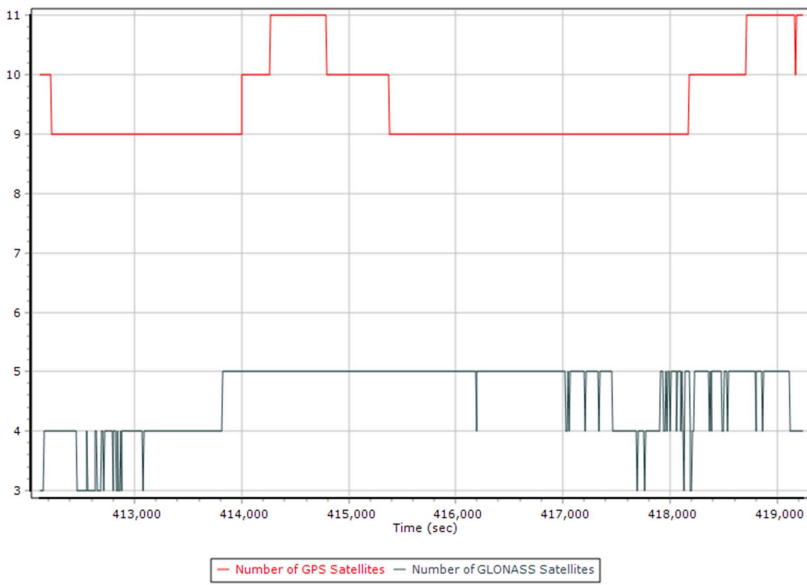
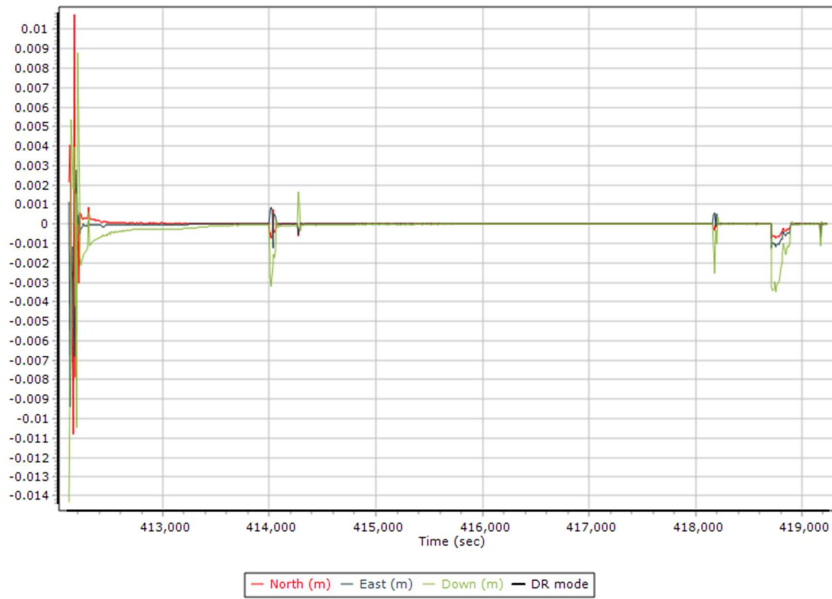
UTC Offset: 18.000

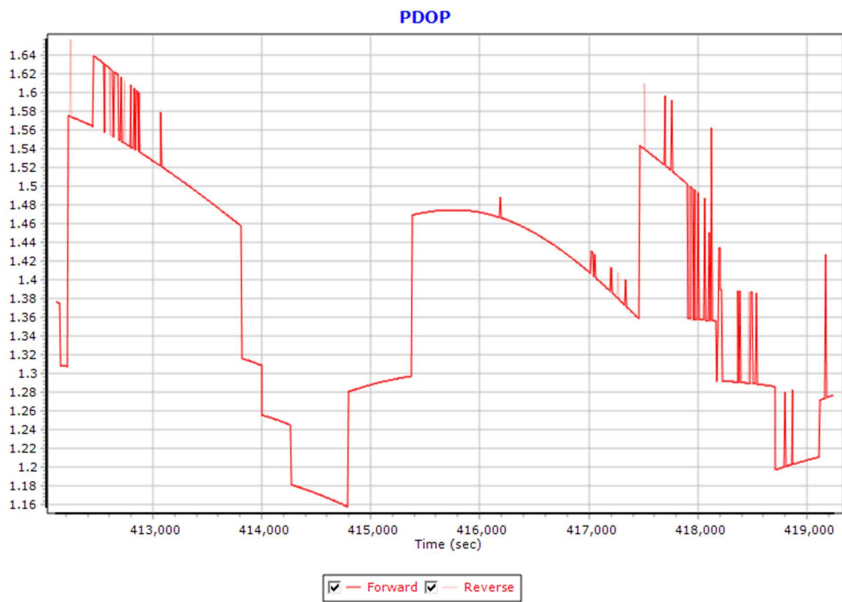
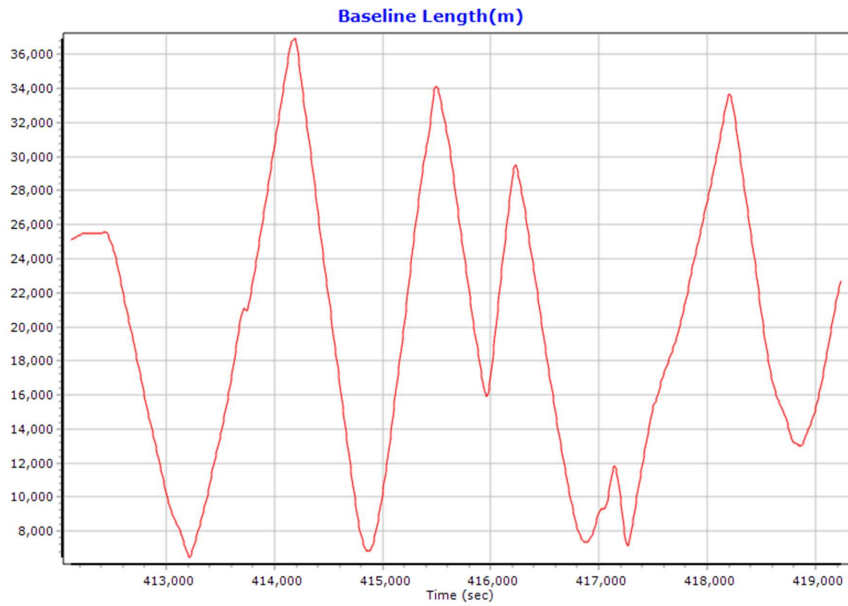
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |



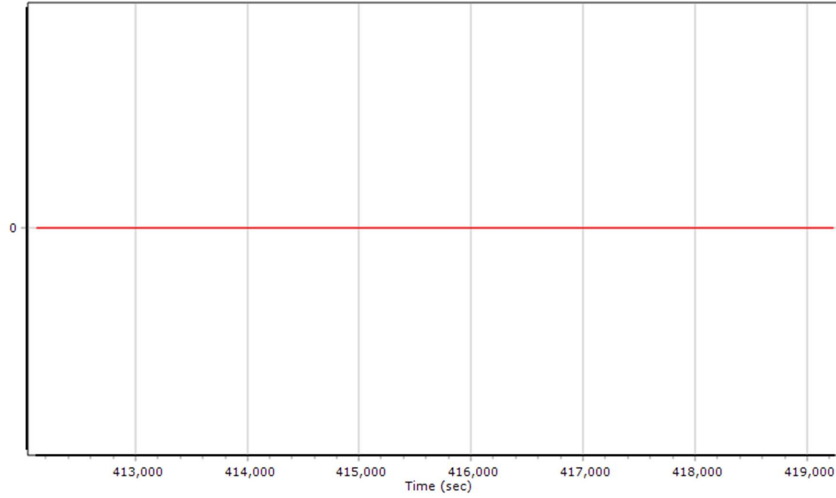






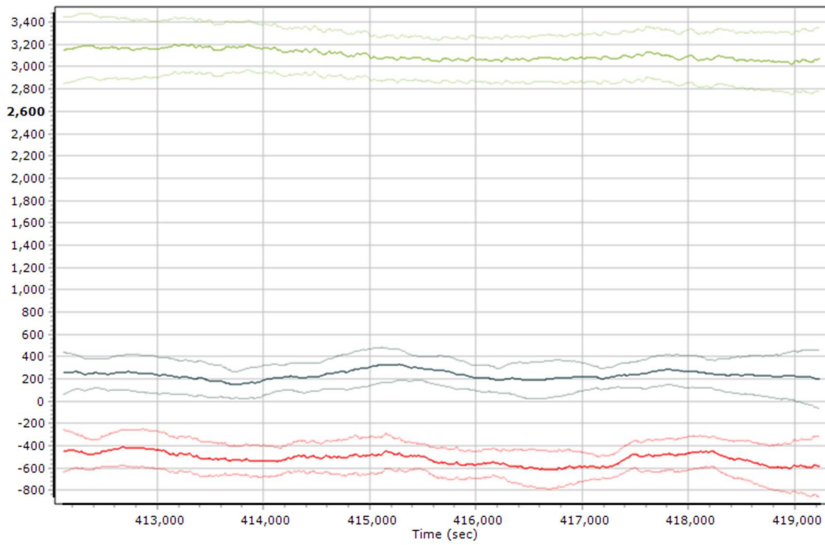


Processing Mode

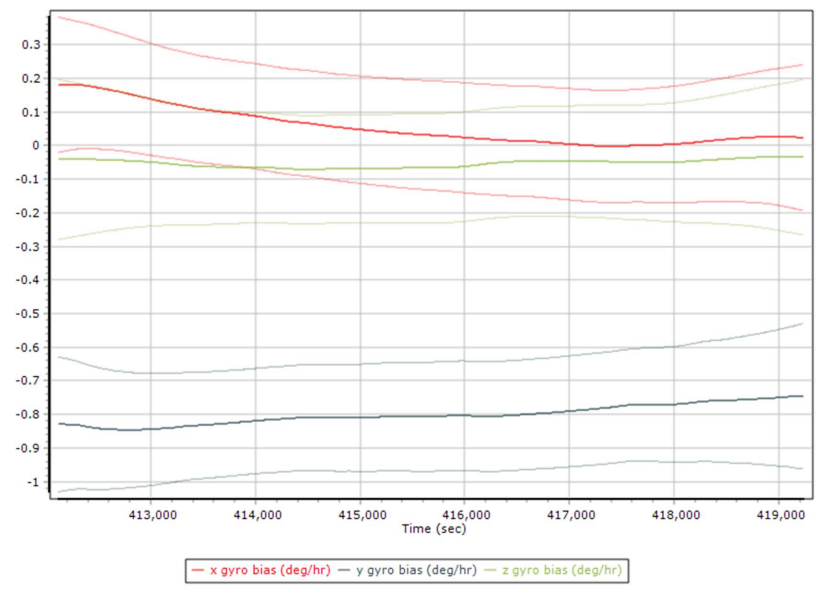
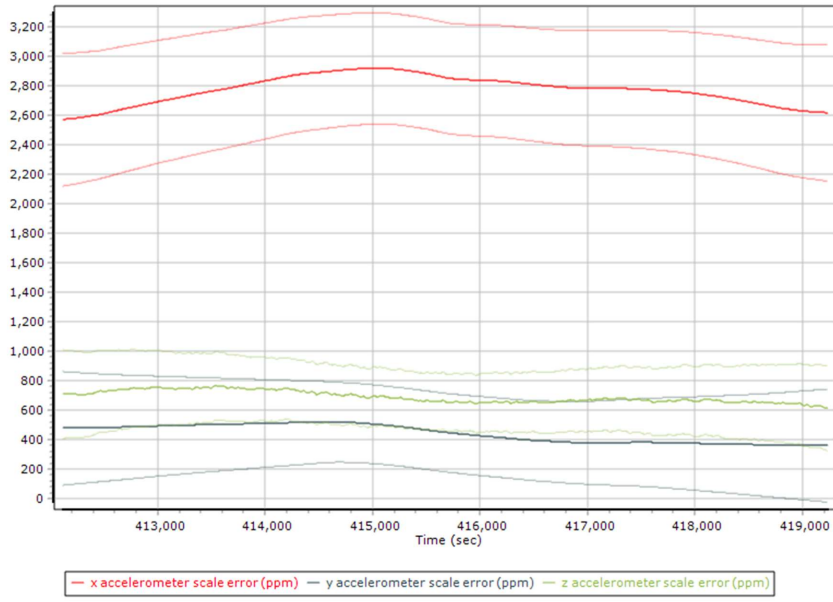


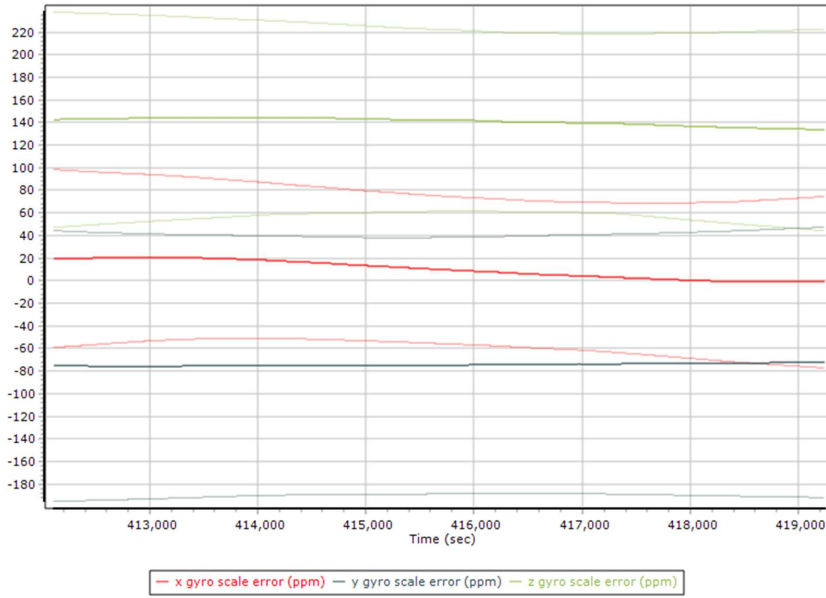
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

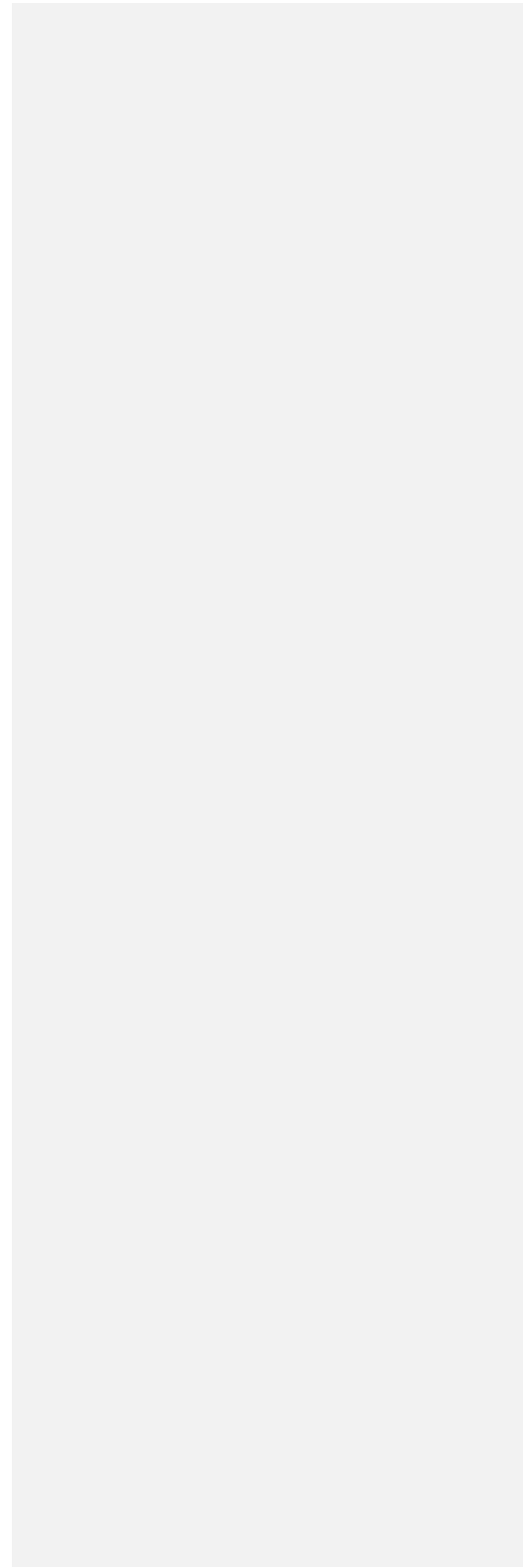
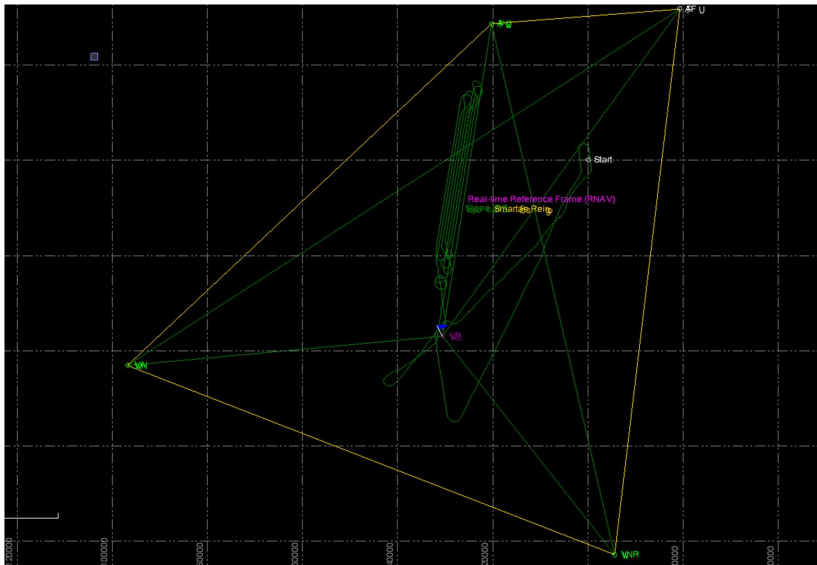


— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



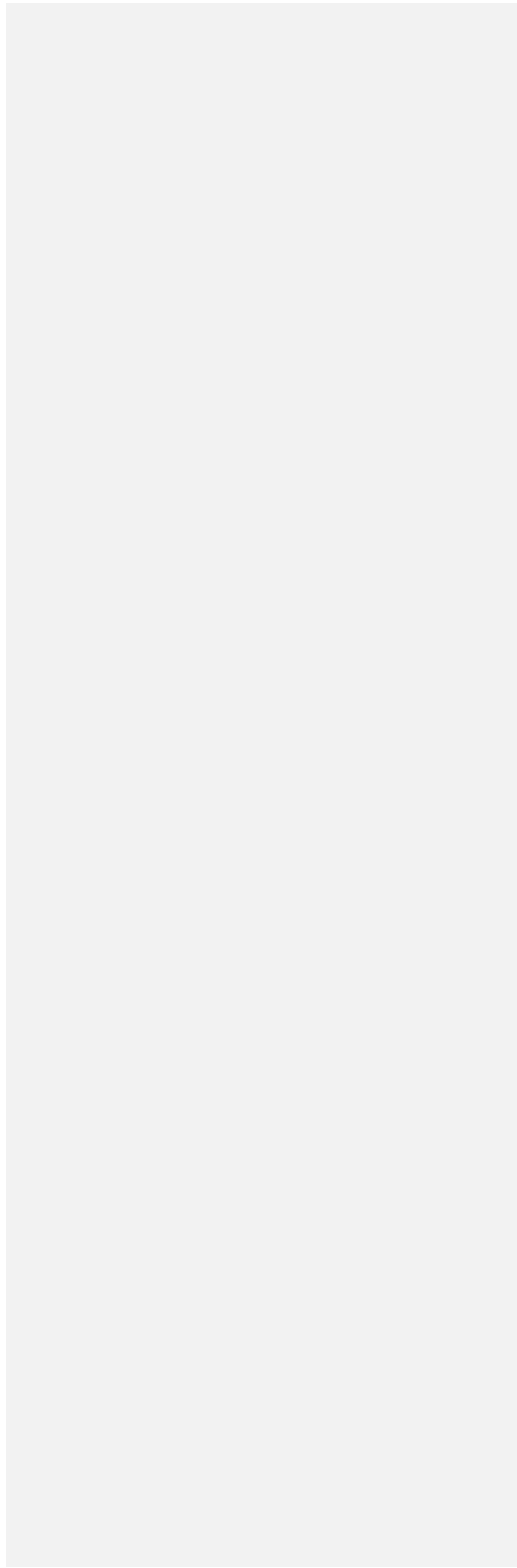


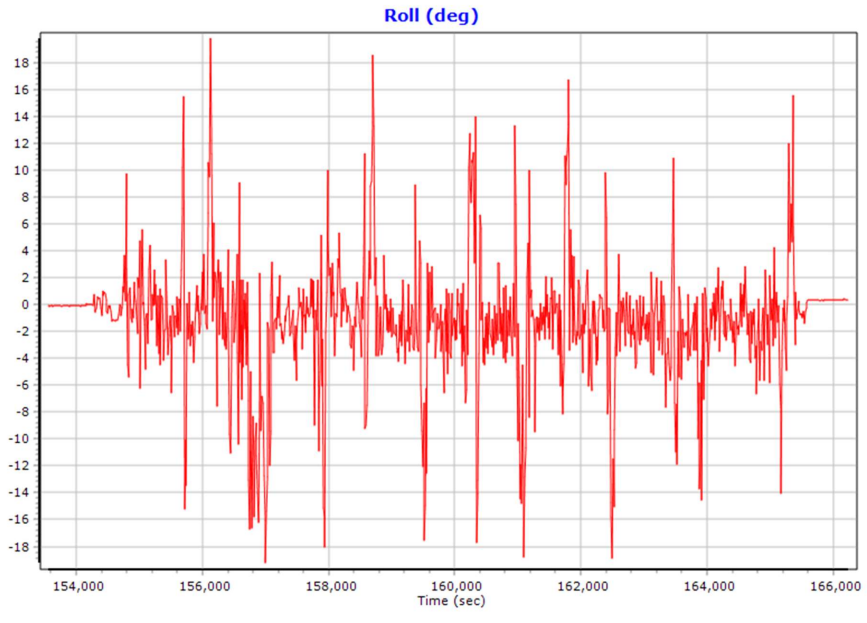
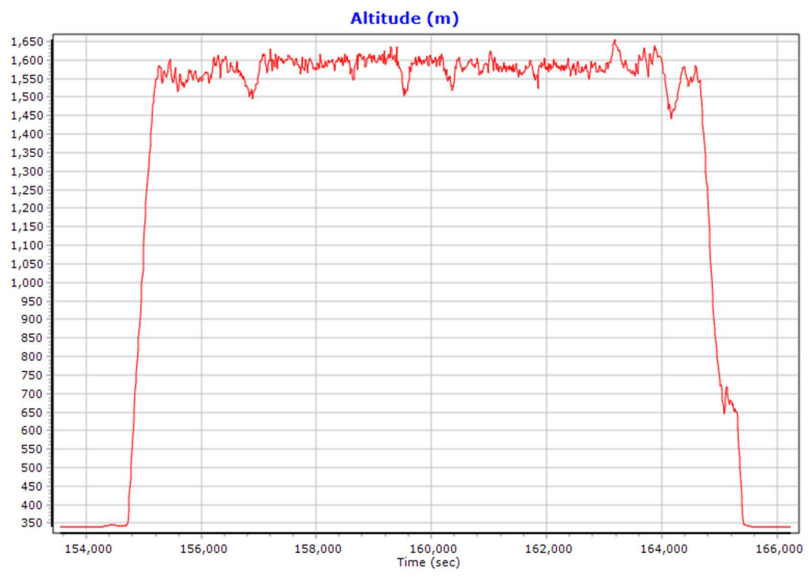
UNB19112A



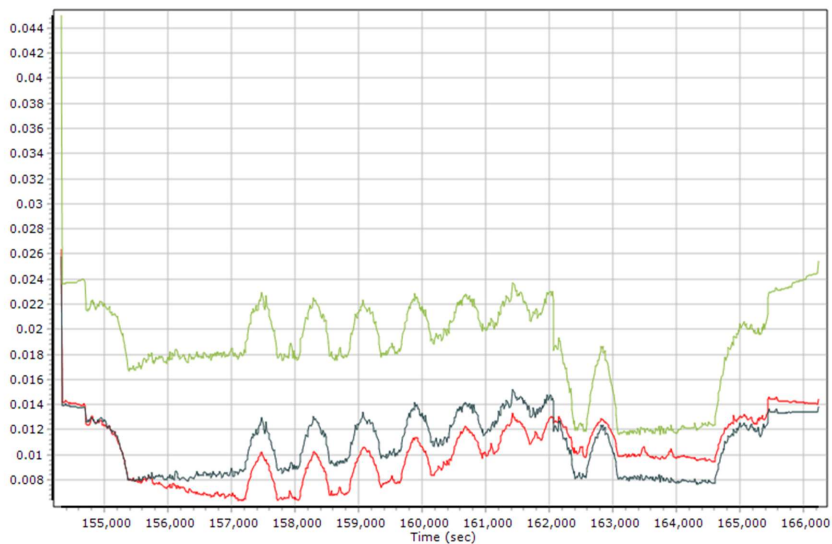
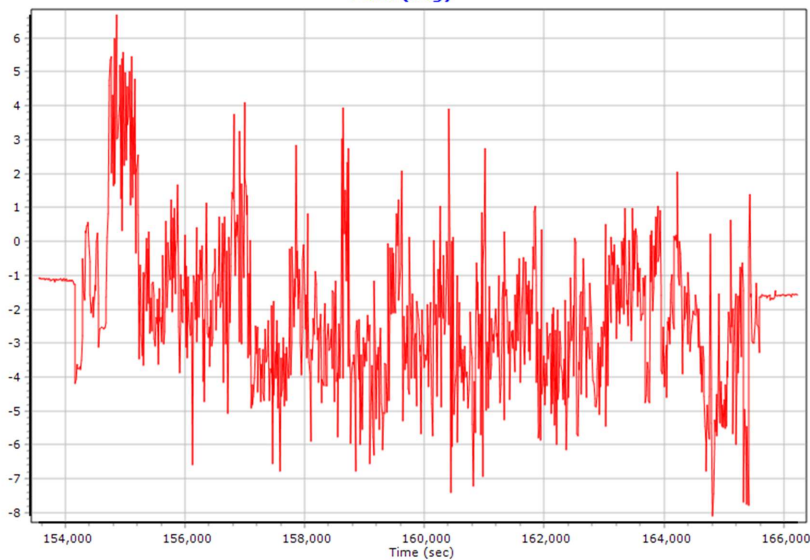
| | | | |
|-------------------------------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|---------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.118 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.062 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.952 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | <input type="range" value="10cm"/> <input type="checkbox"/> <3cm <input type="checkbox"/> 10cm <input type="checkbox"/> 50cm <input type="checkbox"/> 1m <input type="checkbox"/> 10m | | |

| | | | |
|-----------------------------------------------------------|-----------------------------------------|---------------|-------------|
| Timing | | | |
| Start | <input type="text" value="153555.000"/> | Data | Incr. (sec) |
| End | <input type="text" value="166248.000"/> | Output Record | 0.005000 |
| <input checked="" type="checkbox"/> Entire time interval | | IMU | 0.005000 |
| <input checked="" type="checkbox"/> Seconds of start week | | Primary GNSS | 1.000000 |
| UTC Offset | <input type="text" value="18.000"/> | | |

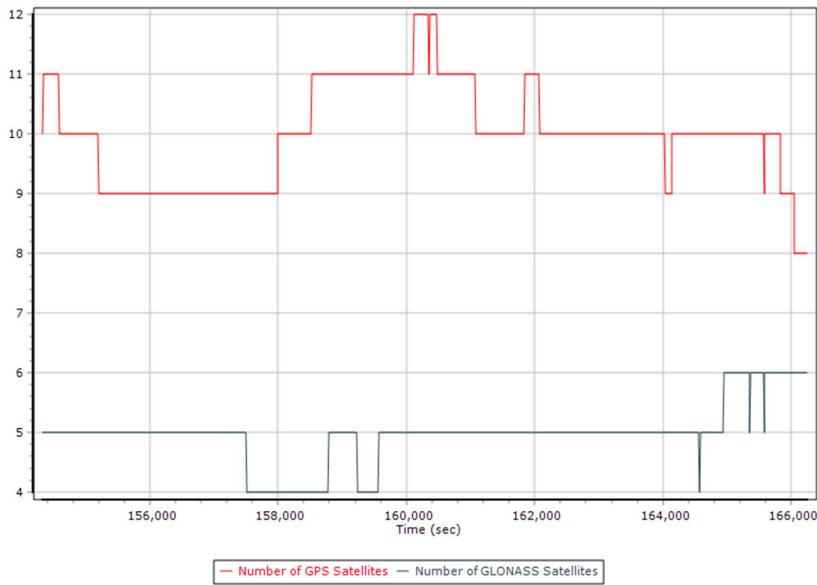




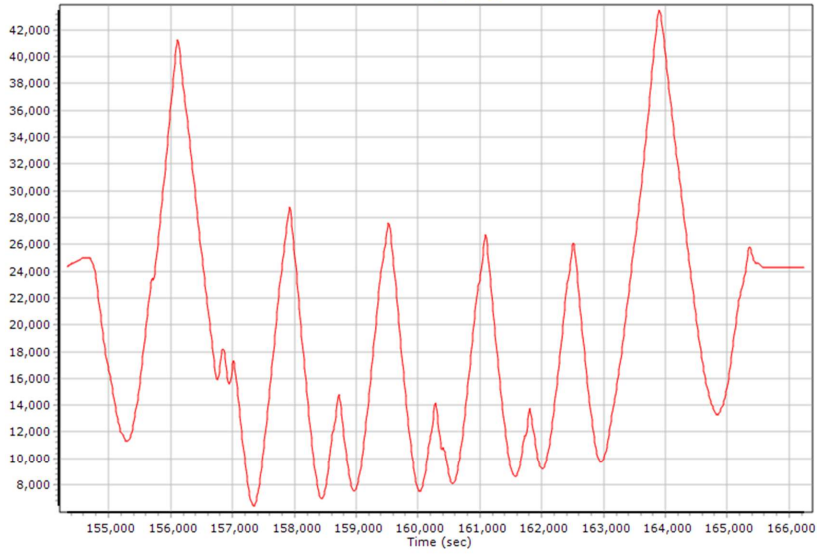
Pitch (deg)



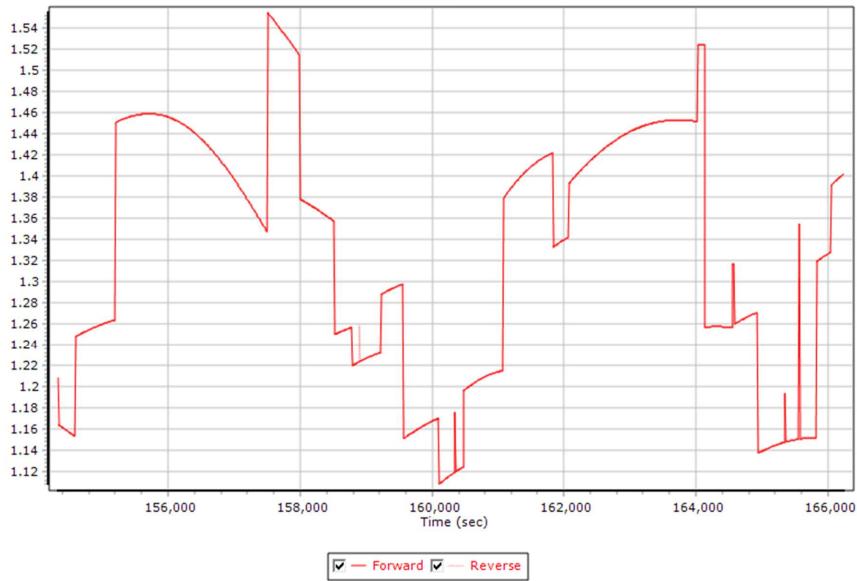
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



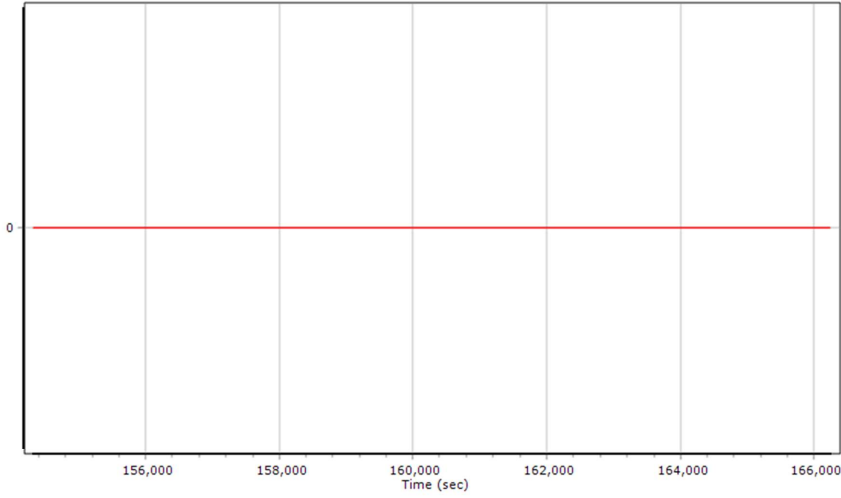
Baseline Length(m)



PDOP

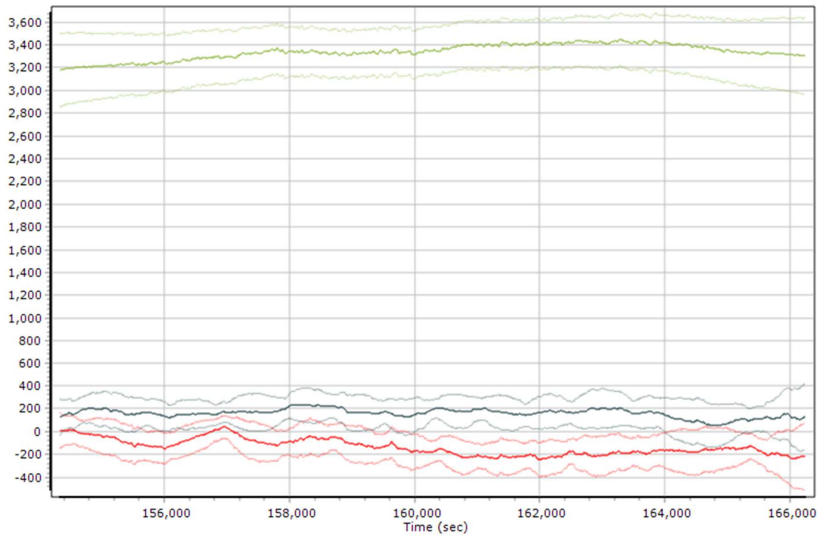


Processing Mode

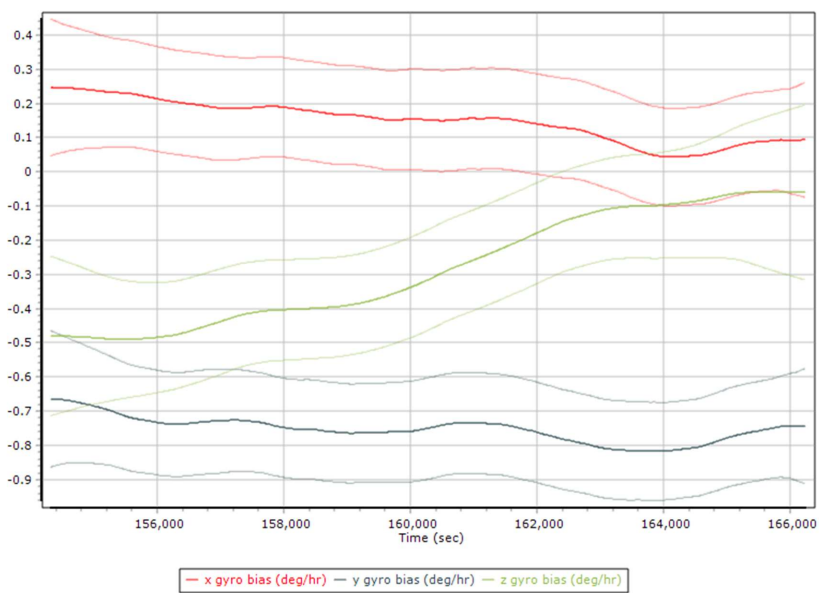
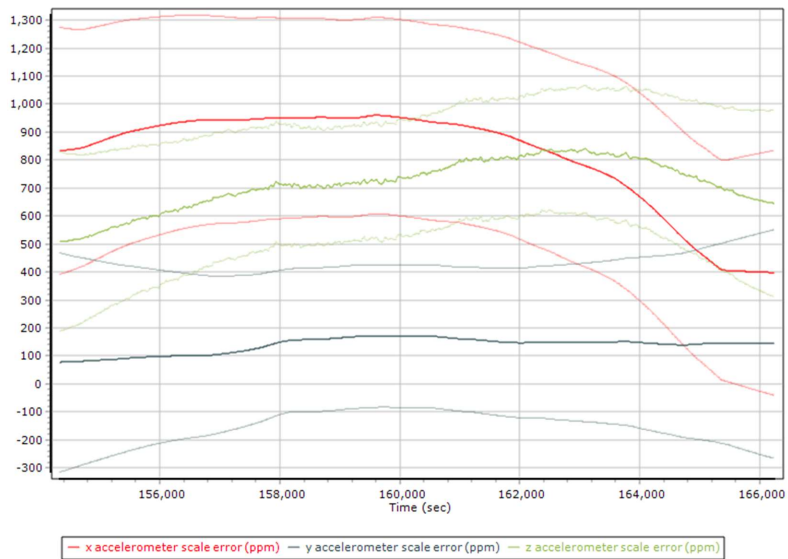


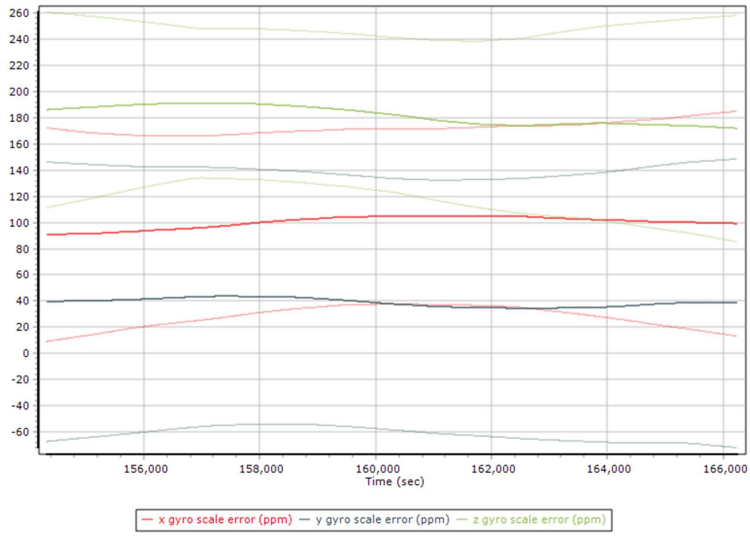
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

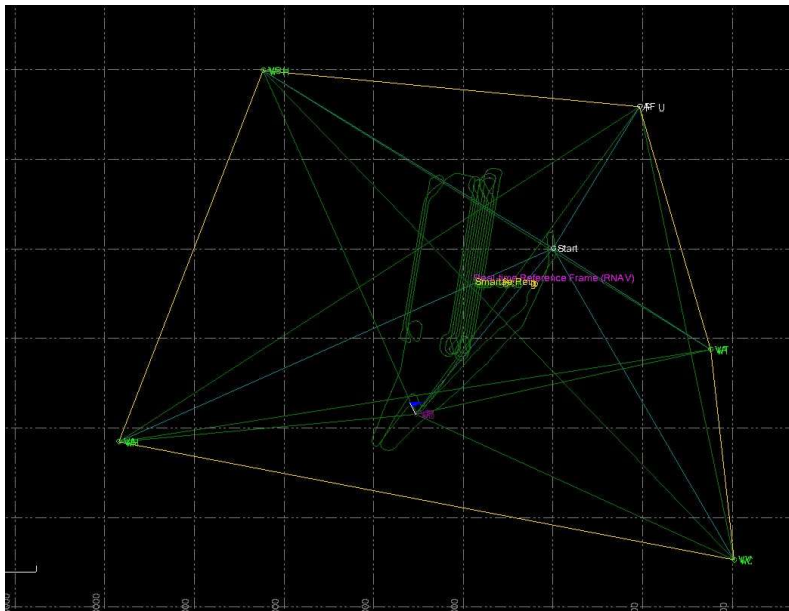


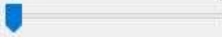
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)



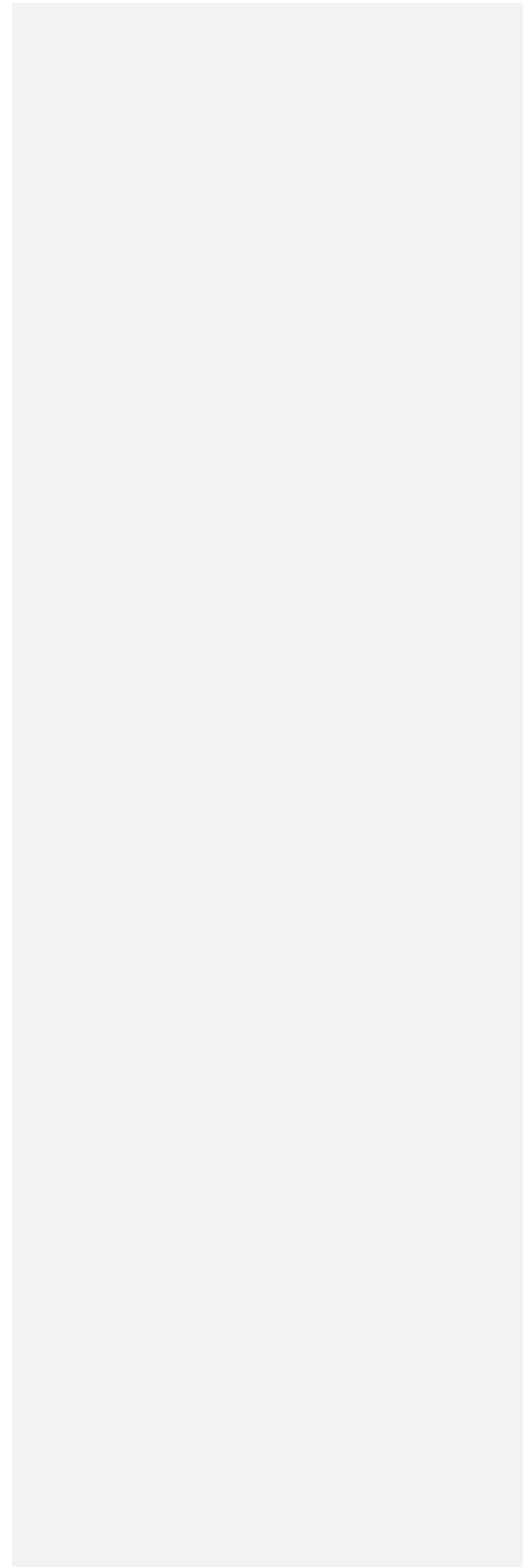


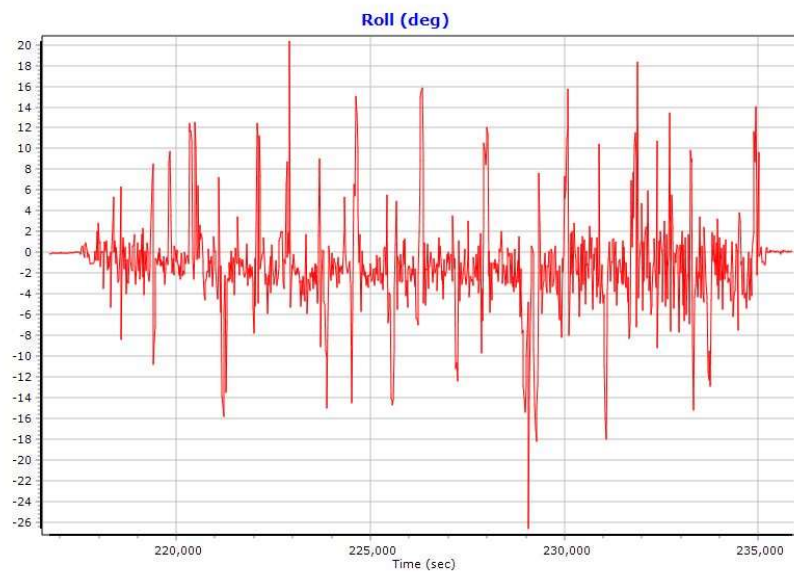
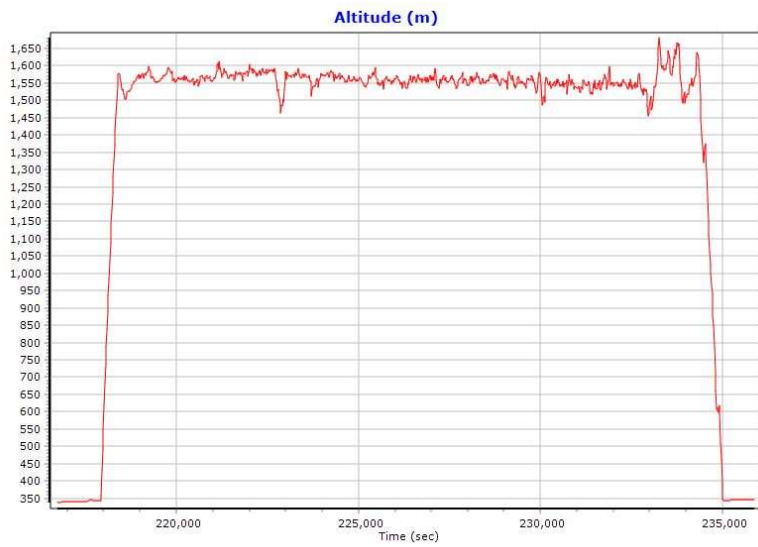
UNB19113A



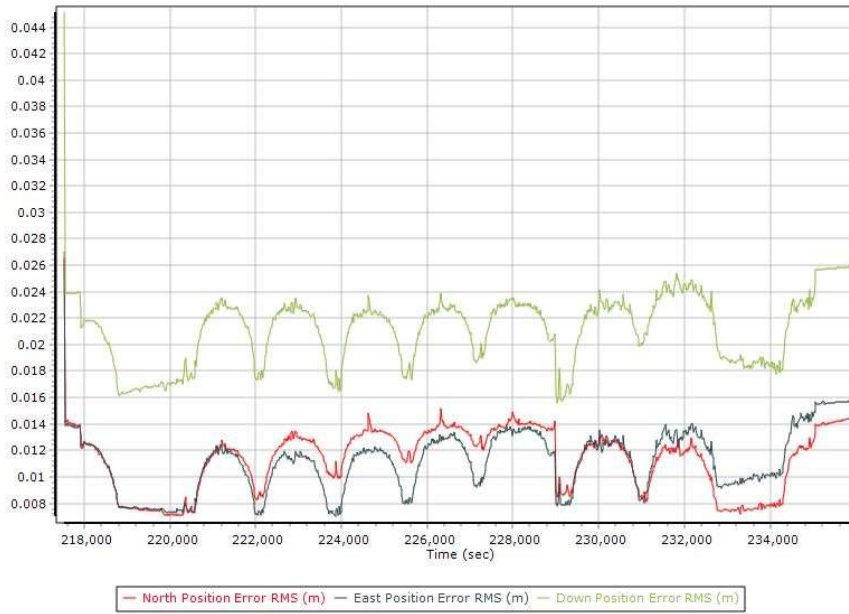
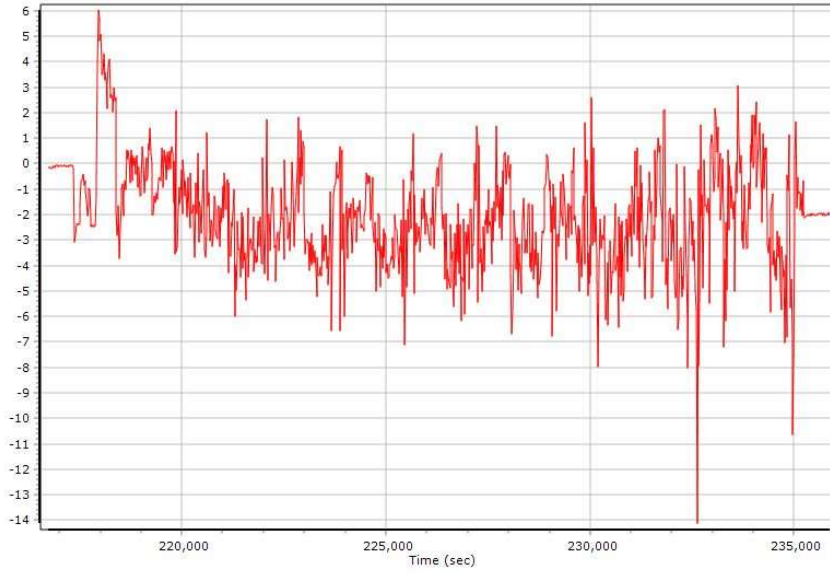
| | | | |
|-------------------------------------|-----------------------------------------------------------------------------------|---------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.118 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.062 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.952 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation |  | | |
| | <3cm 10cm 50cm 1m 10m | | |

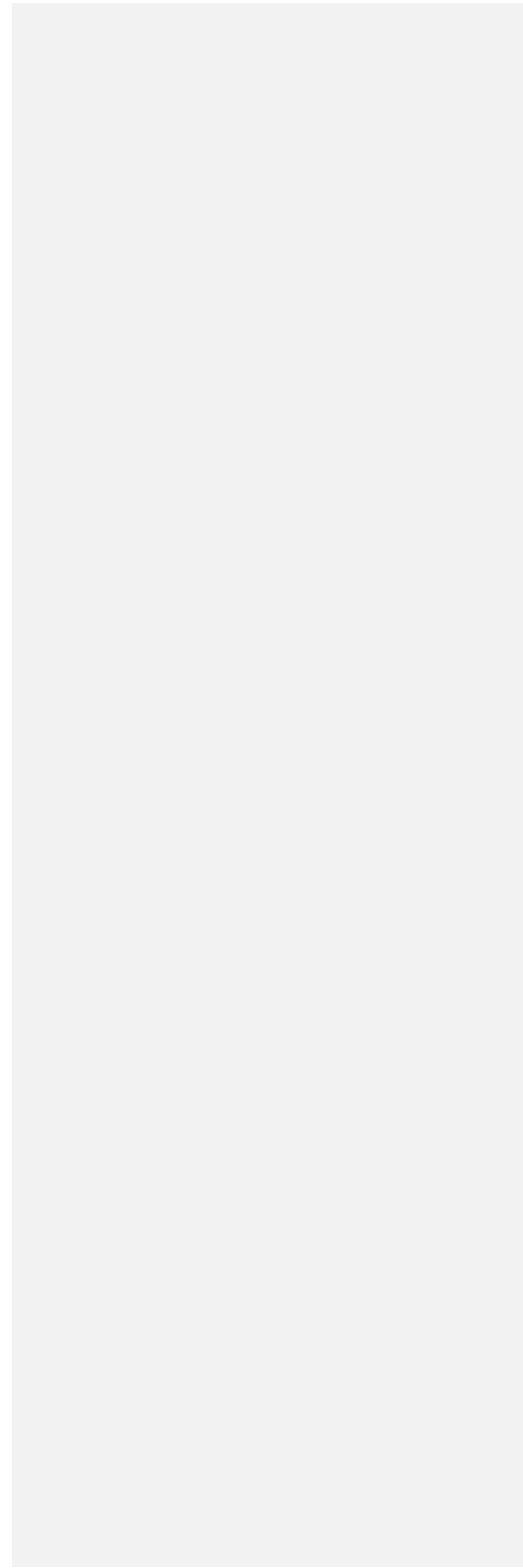
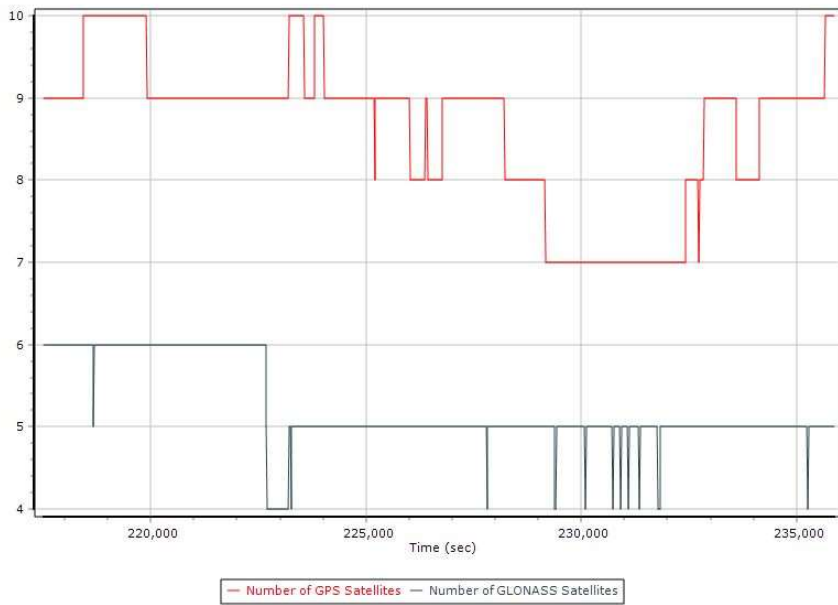
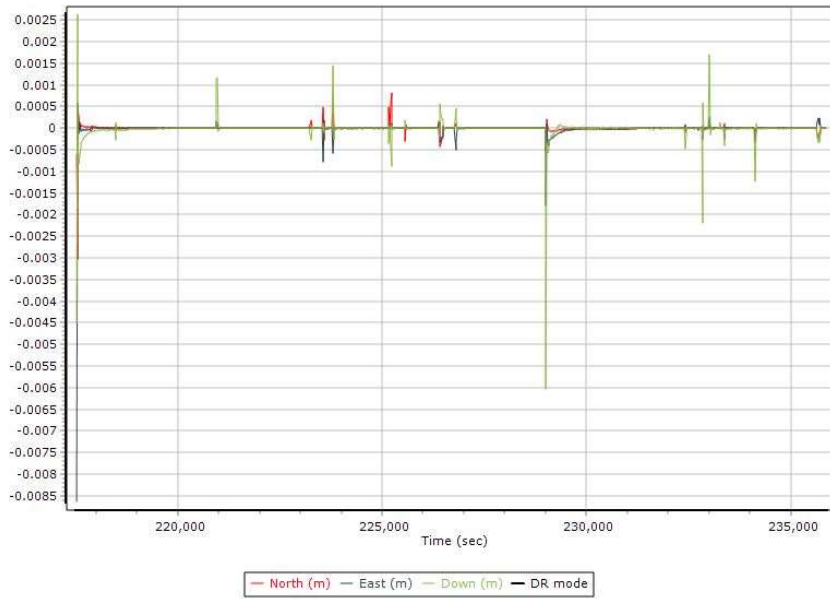
| | | | |
|-------------------------------------|-----------------------------------------|---------------|-------------|
| Timing | | | |
| Start | <input type="text" value="216715.000"/> | Data | Incr. (sec) |
| End | <input type="text" value="235881.000"/> | Output Record | 0.005000 |
| <input checked="" type="checkbox"/> | Entire time interval | IMU | 0.005000 |
| <input checked="" type="checkbox"/> | Seconds of start week | Primary GNSS | 1.000000 |
| UTC Offset | <input type="text" value="18.000"/> | | |



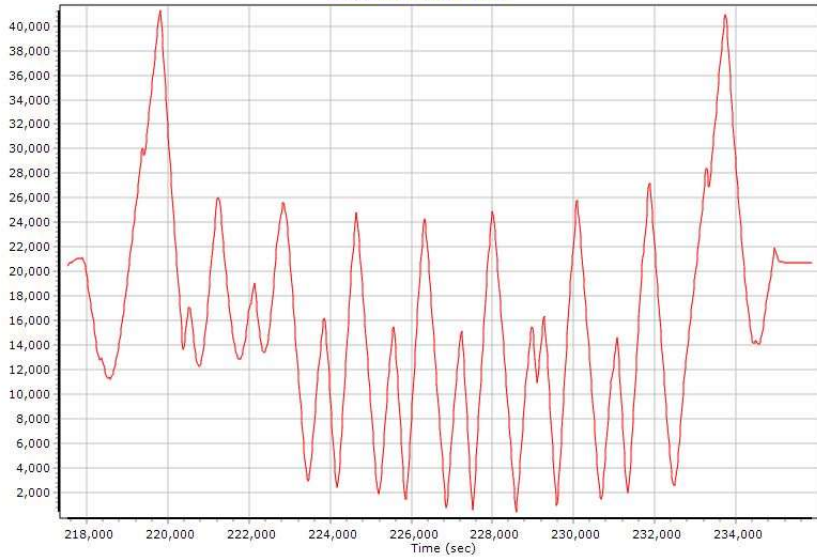


Pitch (deg)

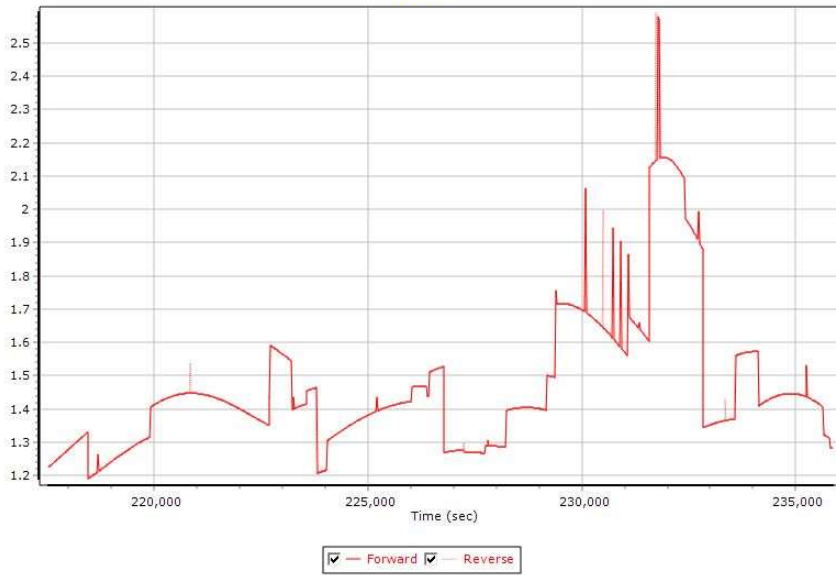




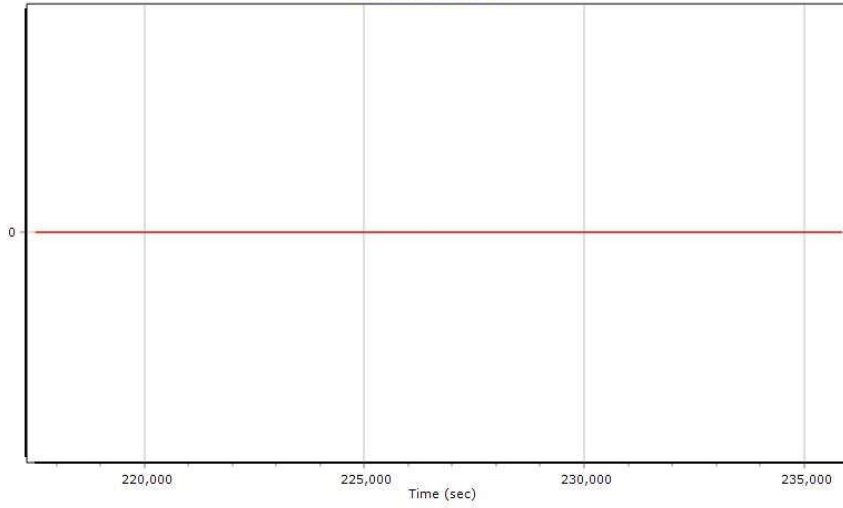
Baseline Length(m)



PDOP

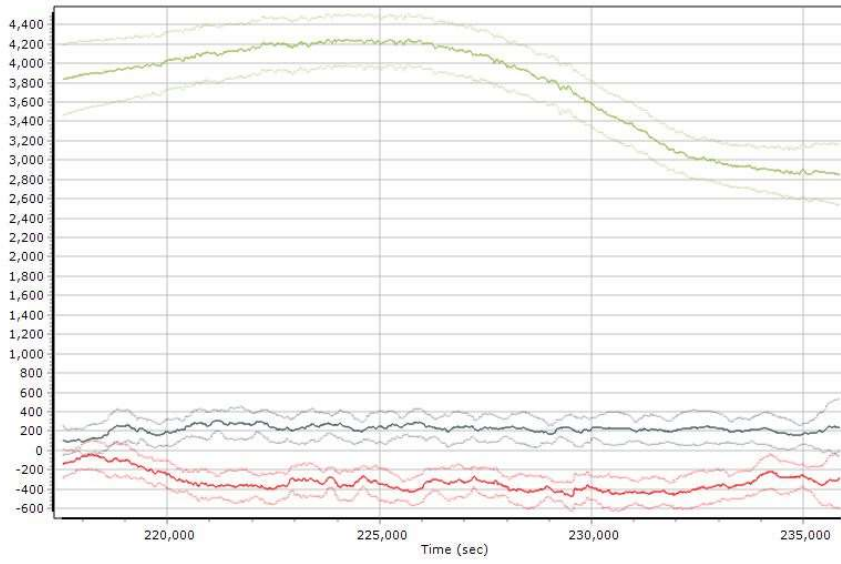


Processing Mode

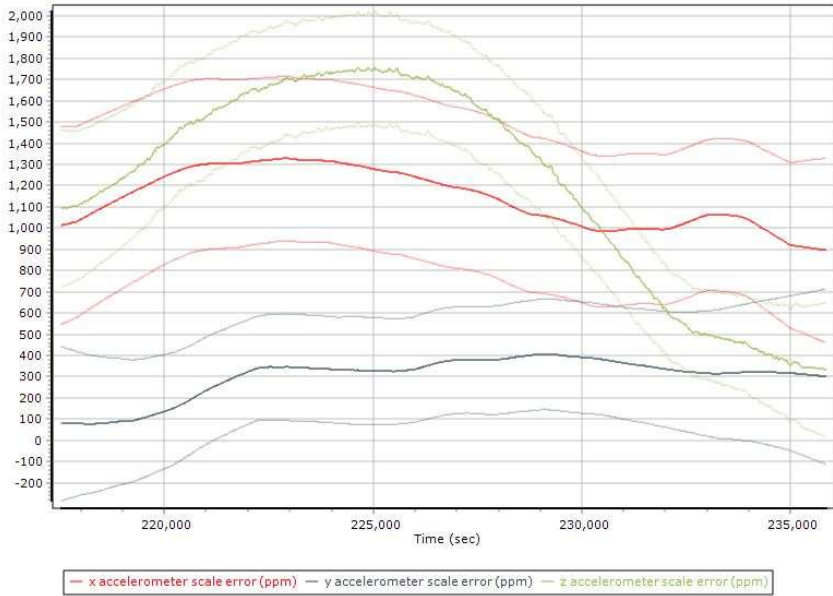


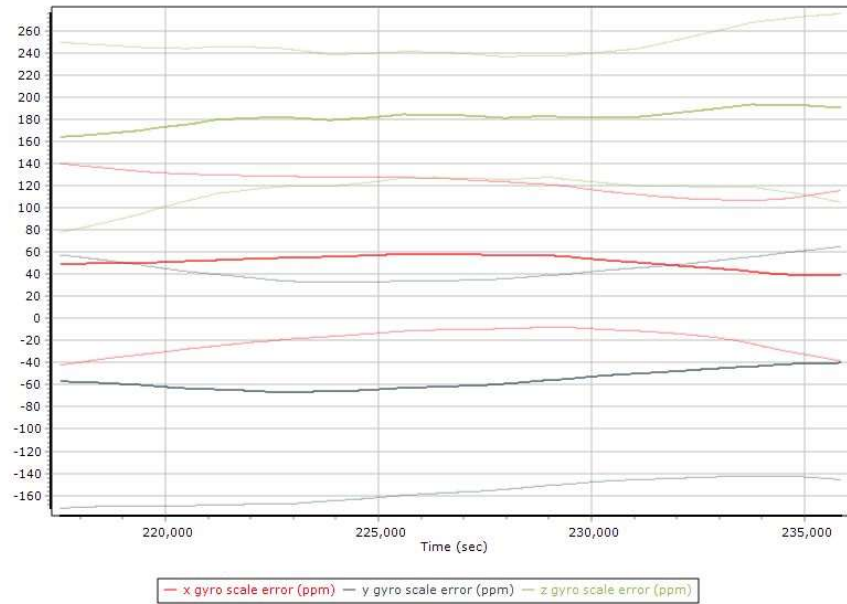
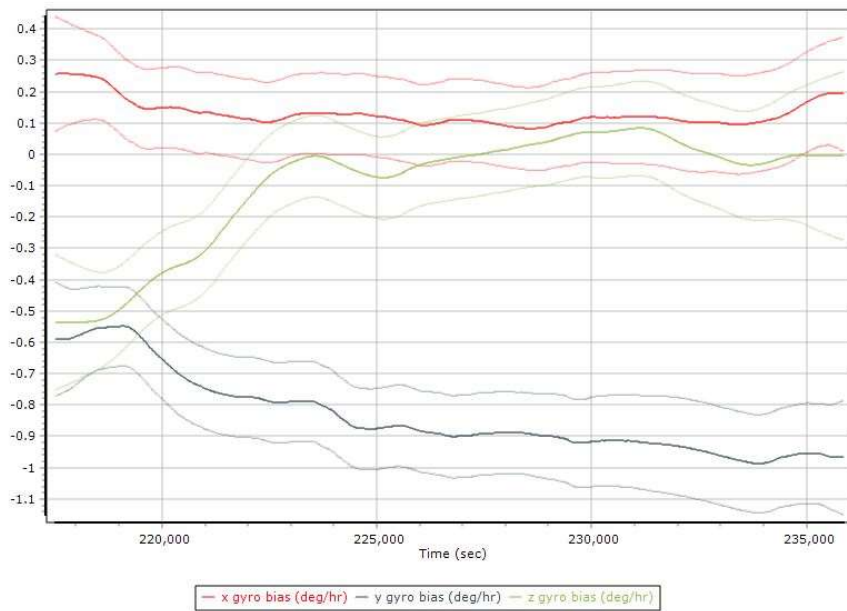
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

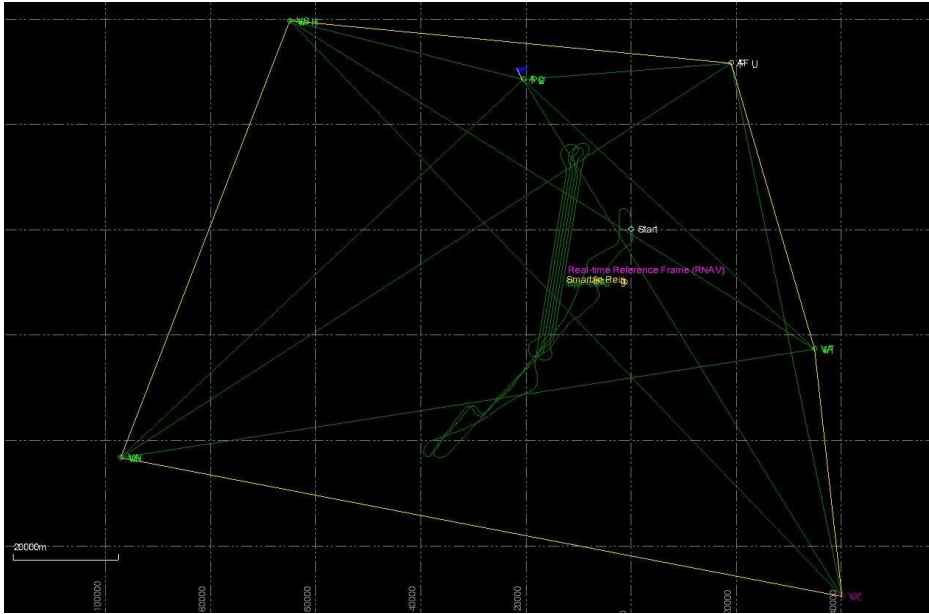


— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)





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| | | | |
|-------------------------------------|---------------------------------------|---------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.118 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.062 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.952 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | <input type="range" value="3"/> | | |
| | <3cm 10cm 50cm 1m 10m | | |

Timing

Start: 240410.000

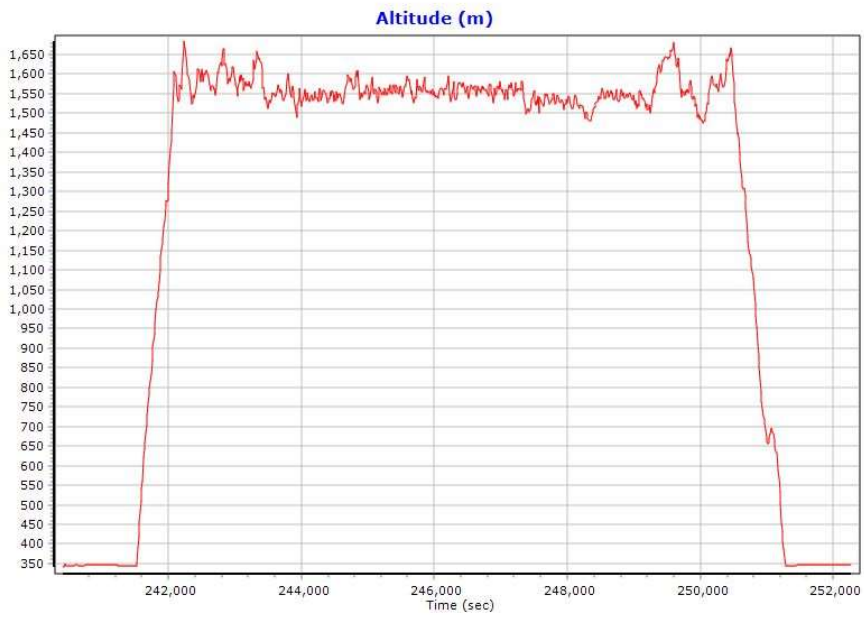
End: 252267.000

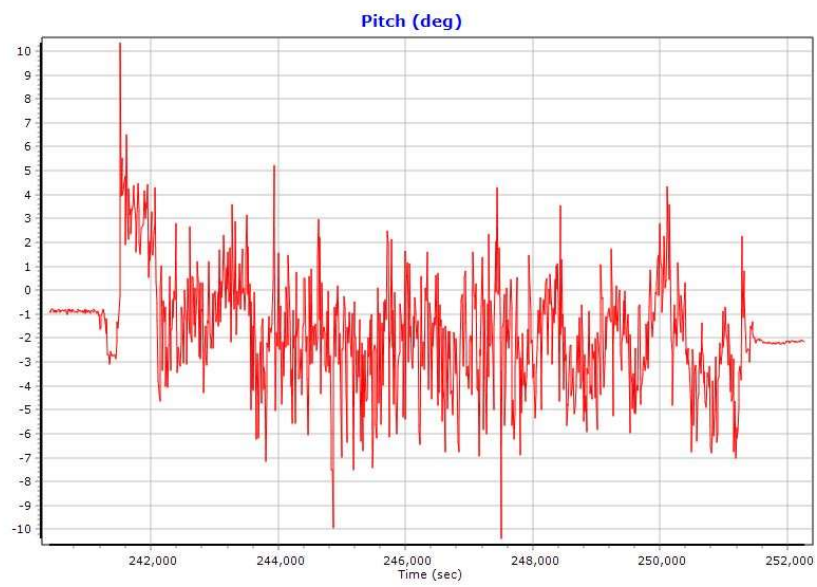
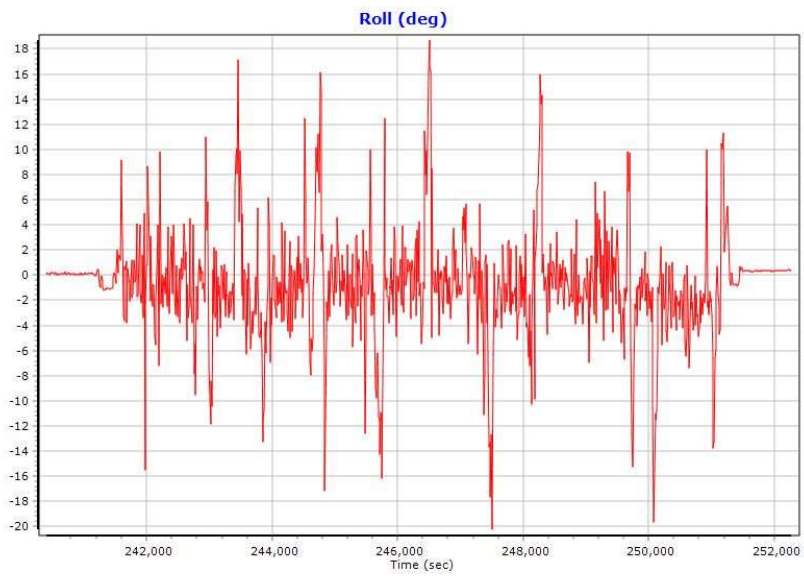
Entire time interval

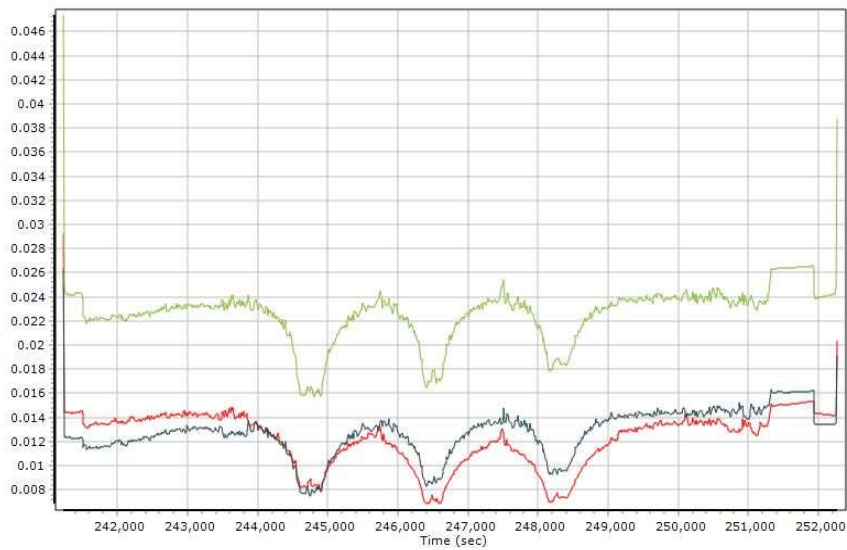
Seconds of start week

UTC Offset: 18.000

| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |



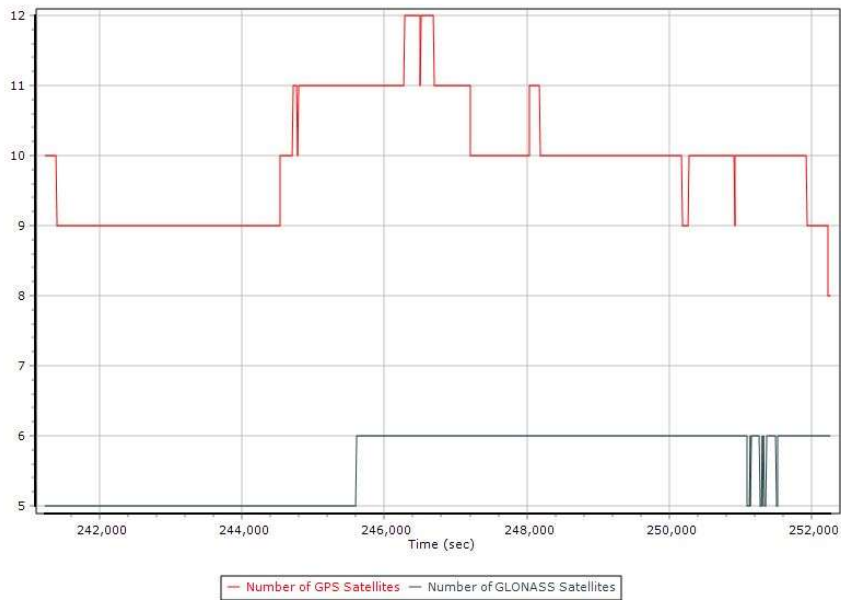




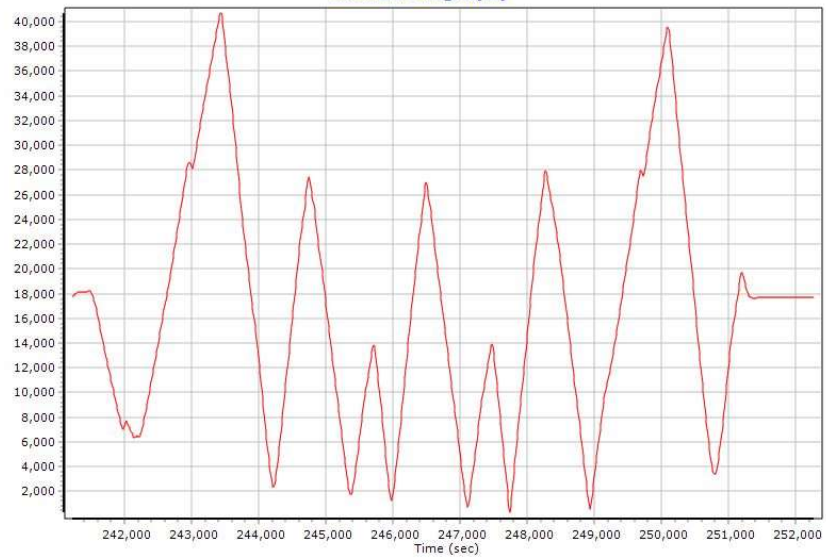
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



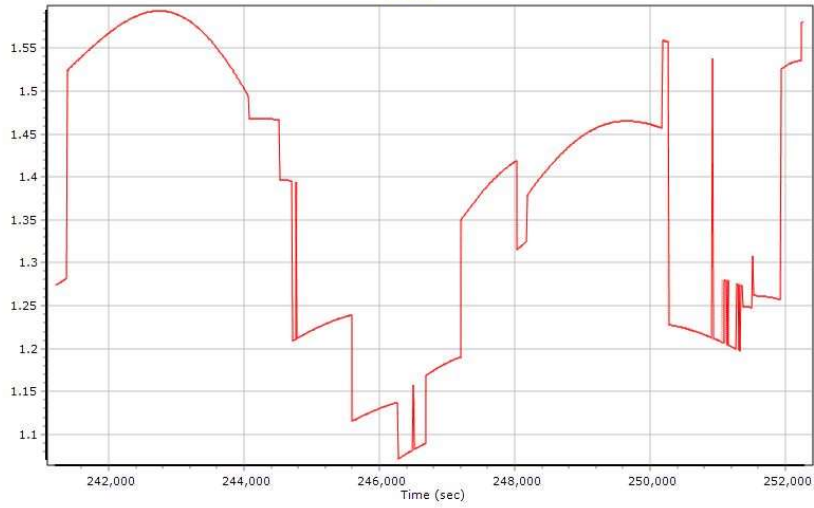
— North (m) — East (m) — Down (m) — DR mode



Baseline Length(m)

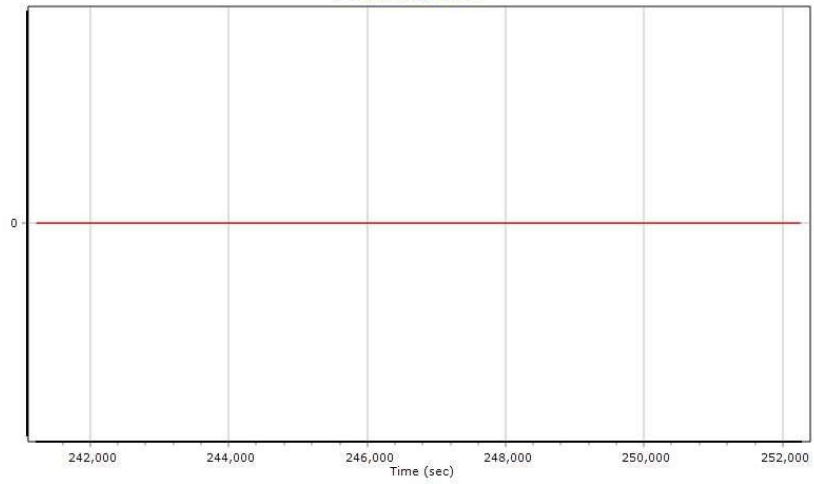


PDOP



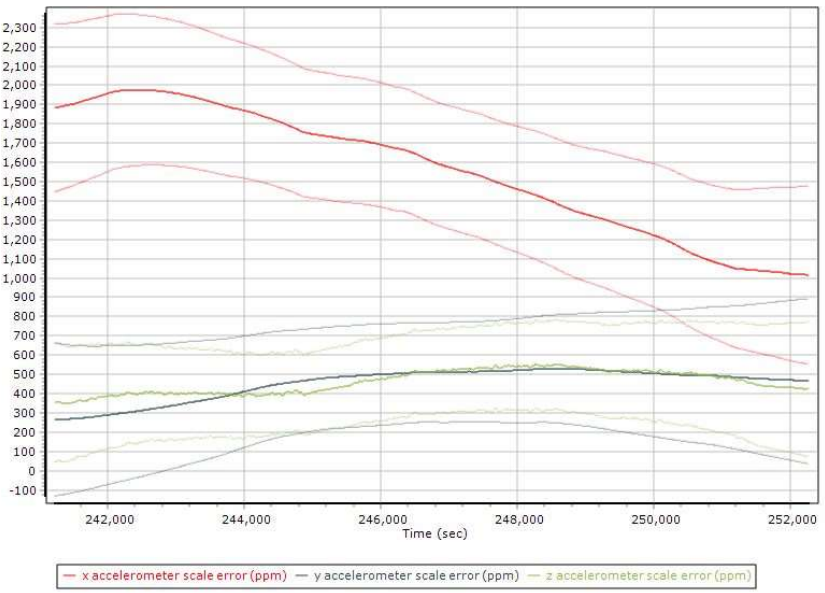
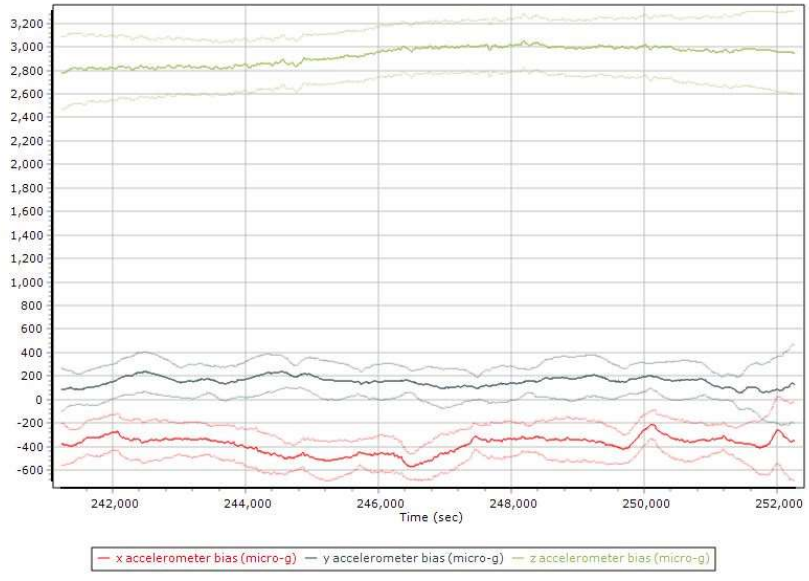
Forward Reverse

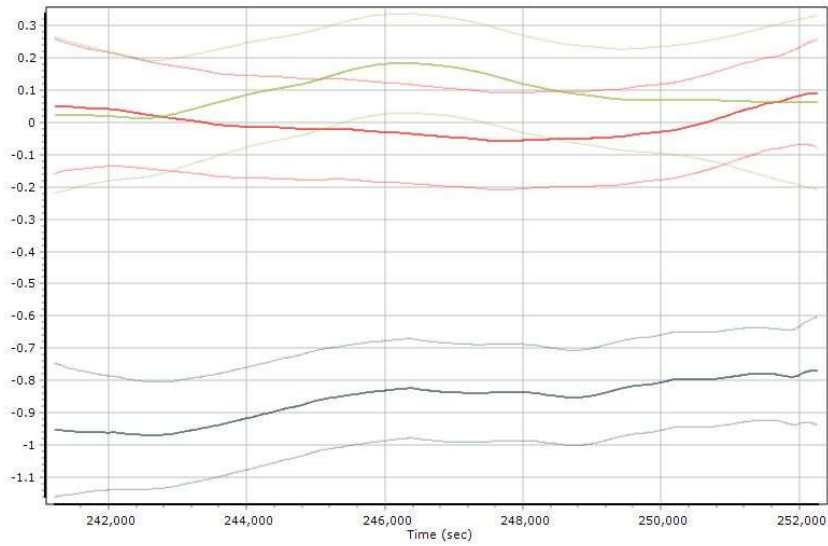
Processing Mode



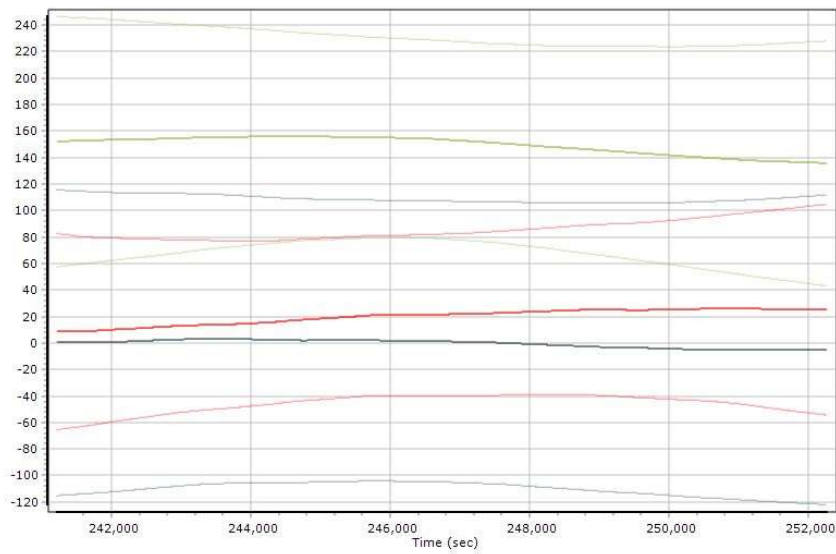
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



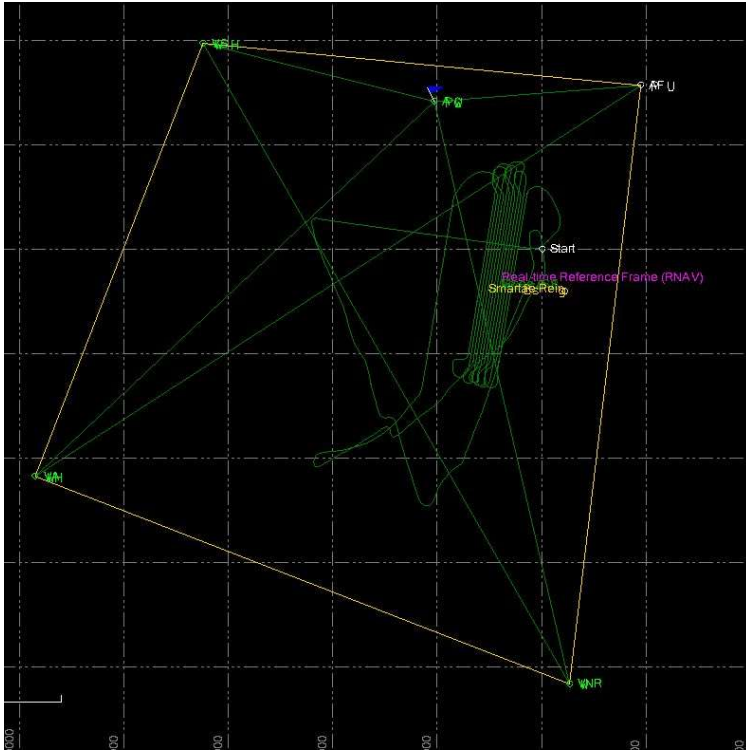


x gyro bias (deg/hr) y gyro bias (deg/hr) z gyro bias (deg/hr)

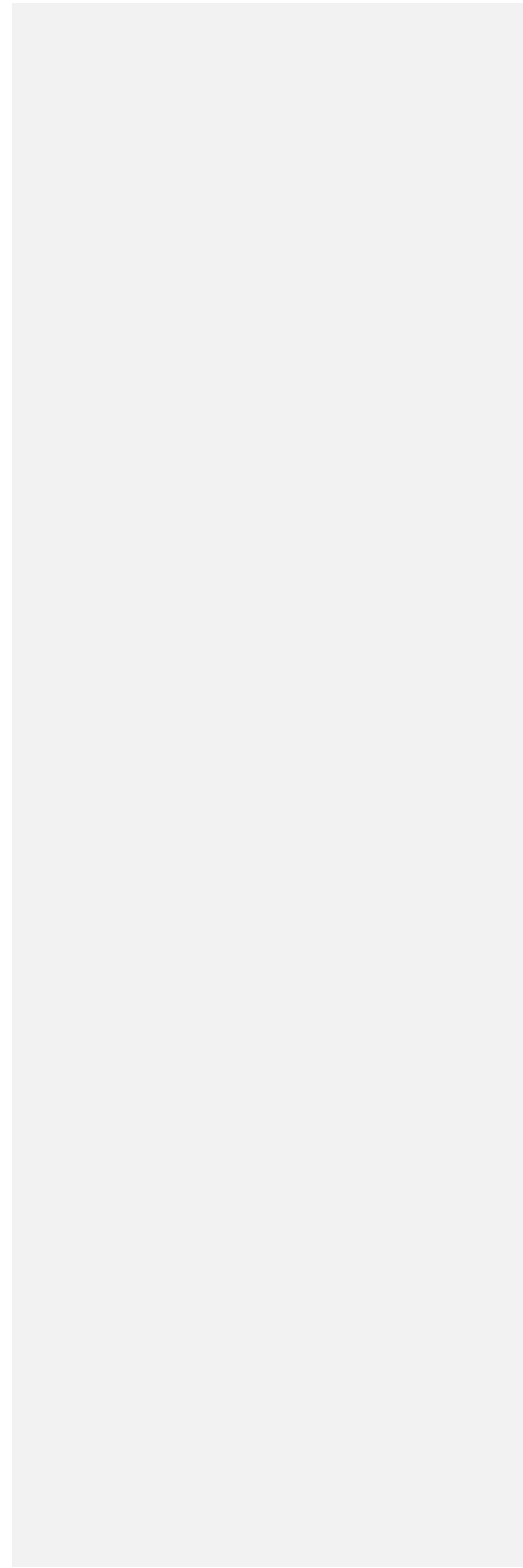


x gyro scale error (ppm) y gyro scale error (ppm) z gyro scale error (ppm)

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| | | | |
|-------------------------------------|---------------------------------------|---------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.118 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.062 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.952 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | <input type="range" value="0.03"/> | | |
| | <3cm 10cm 50cm 1m 10m | | |



Timing

Start: 314330.000

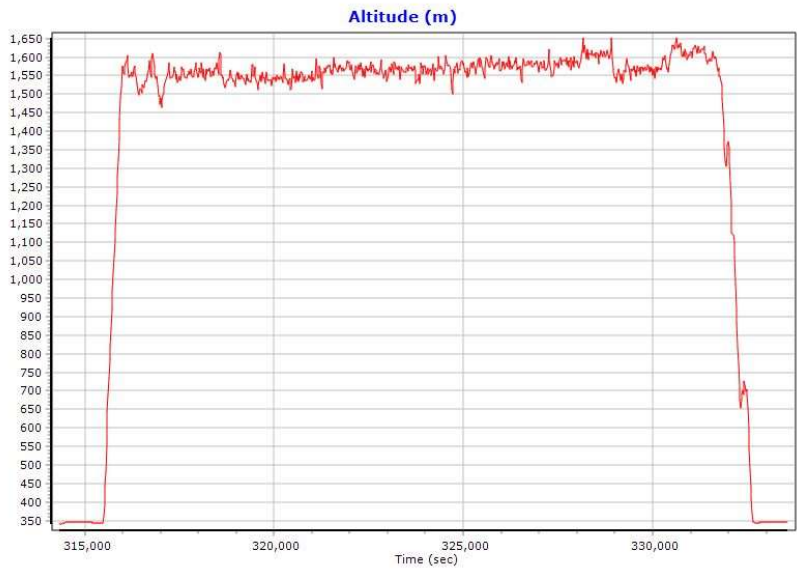
End: 333582.000

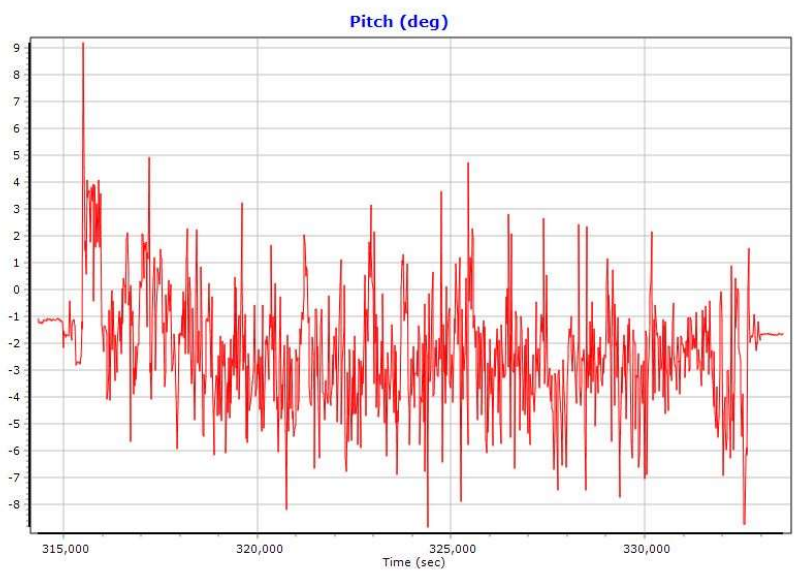
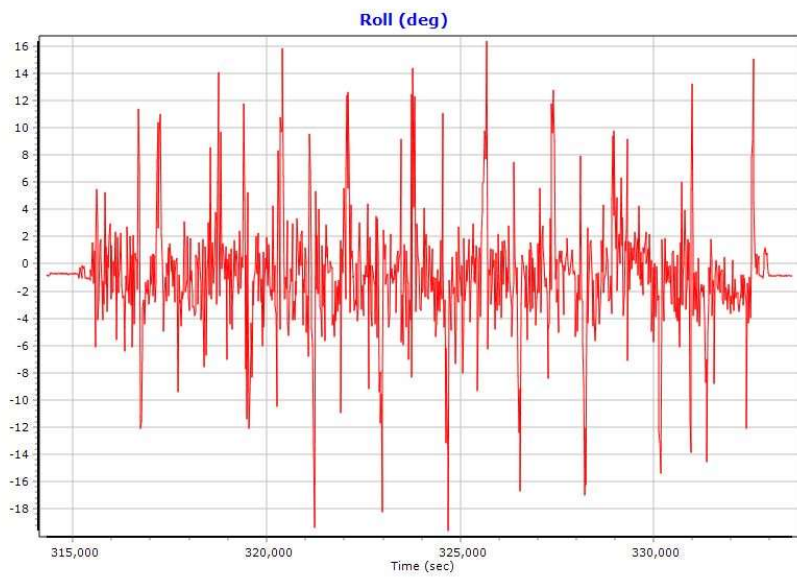
Entire time interval

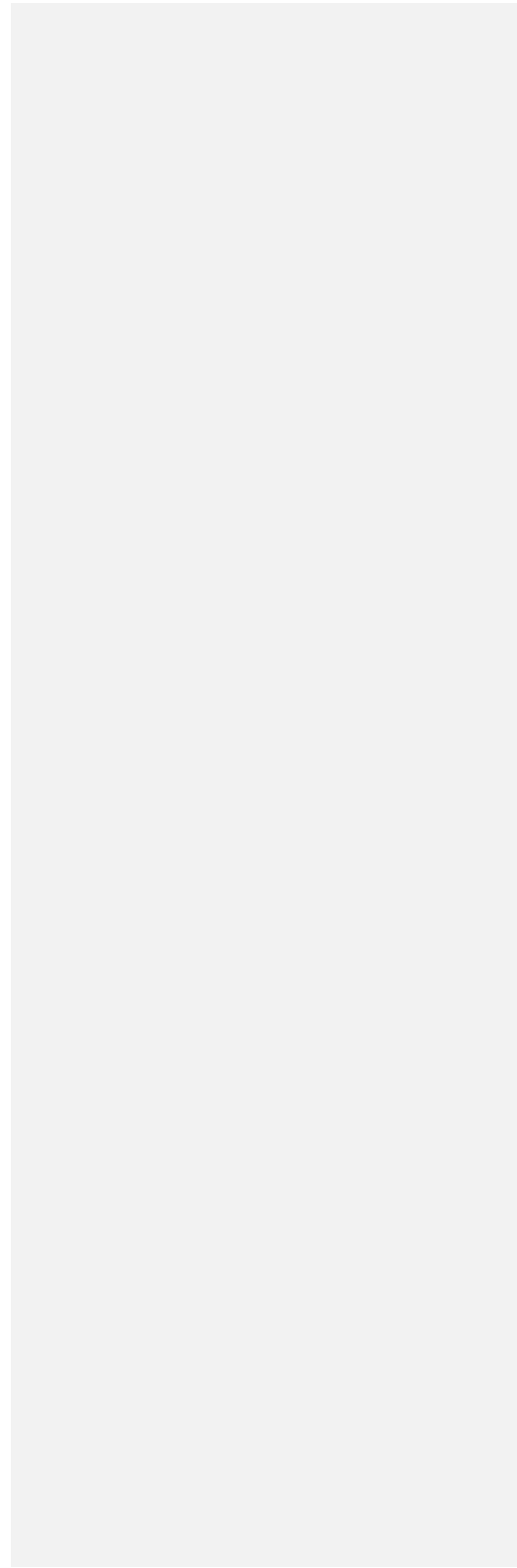
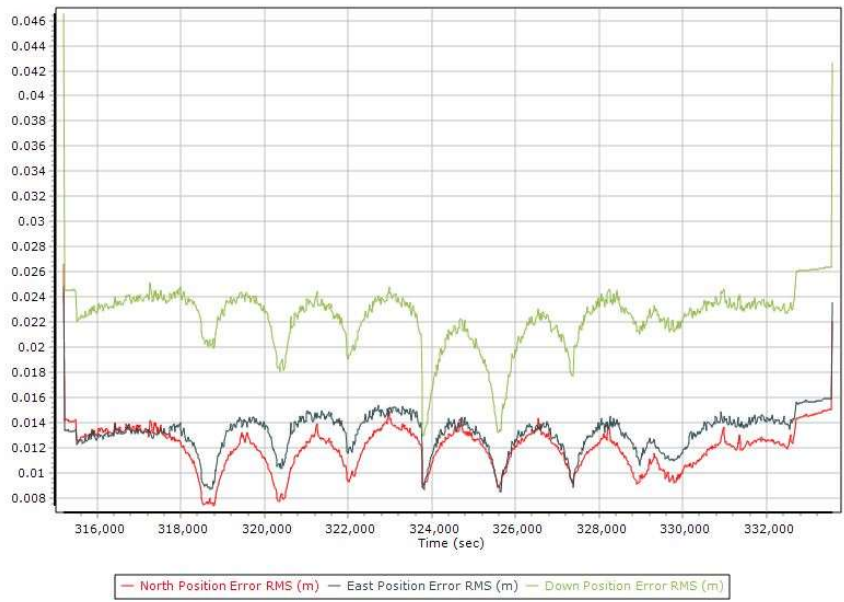
Seconds of start week

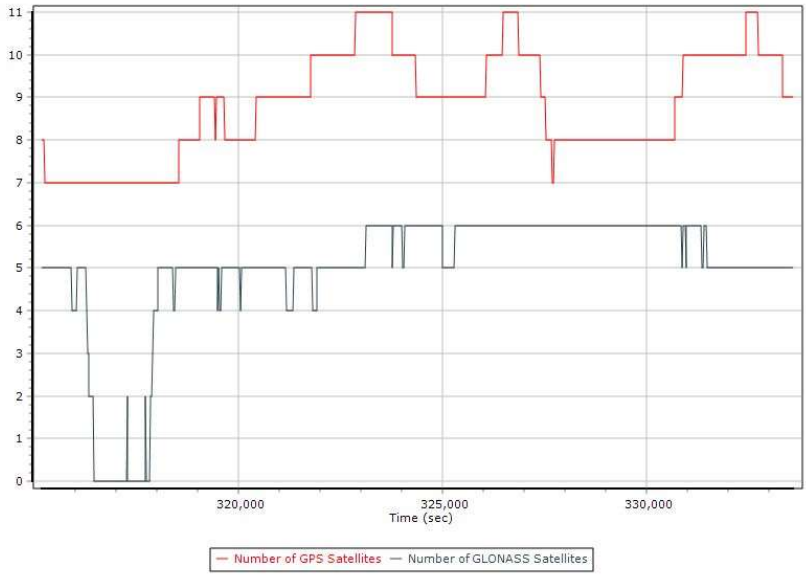
UTC Offset: 18.000

| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

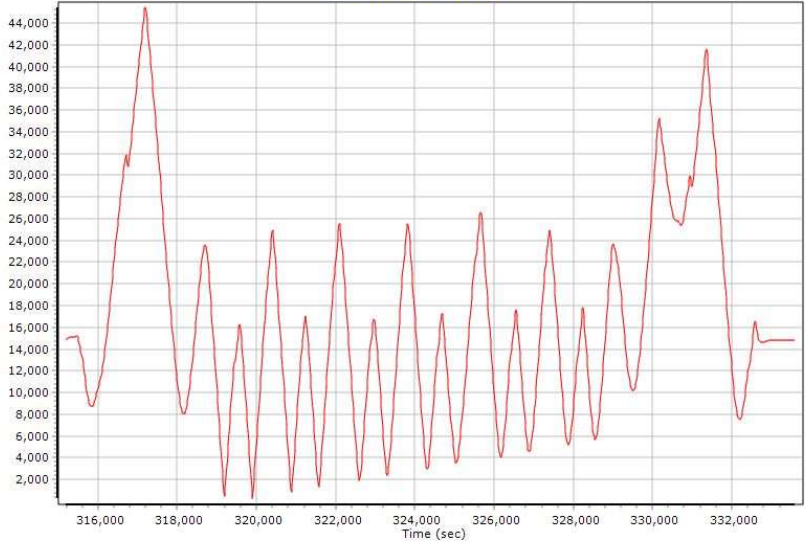




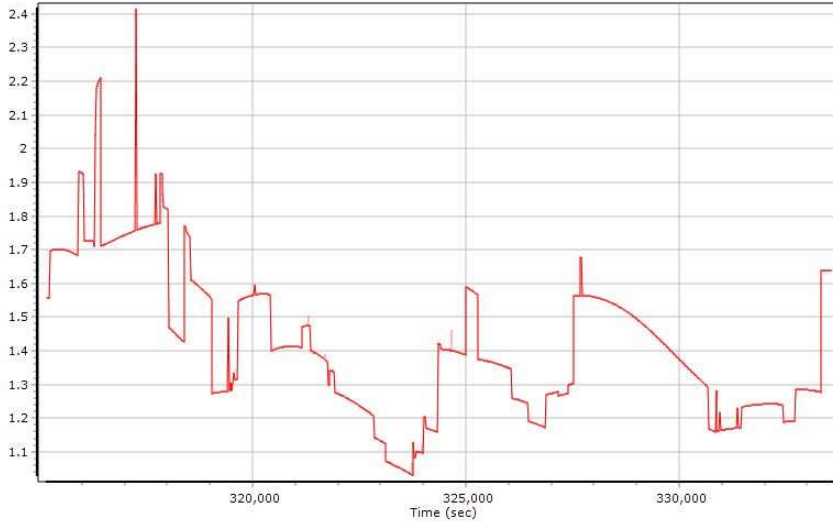




Baseline Length(m)

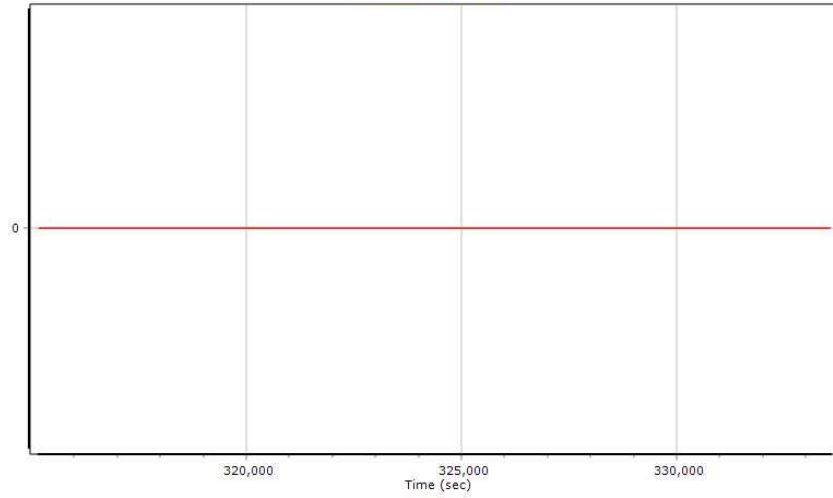


PDOP



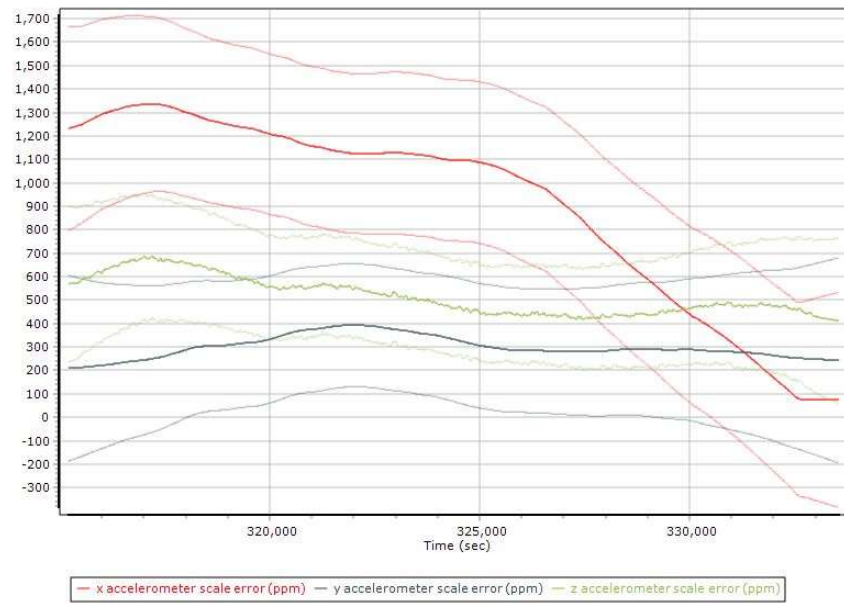
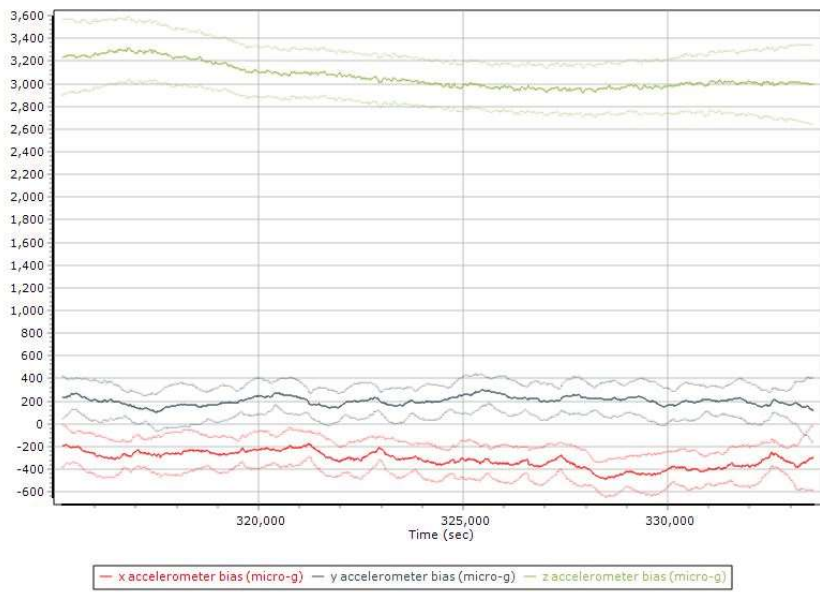
Forward Reverse

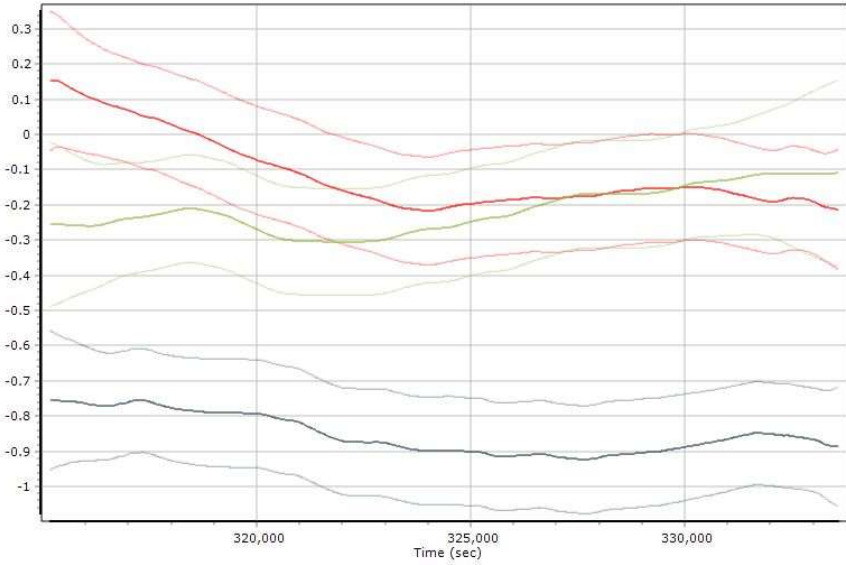
Processing Mode



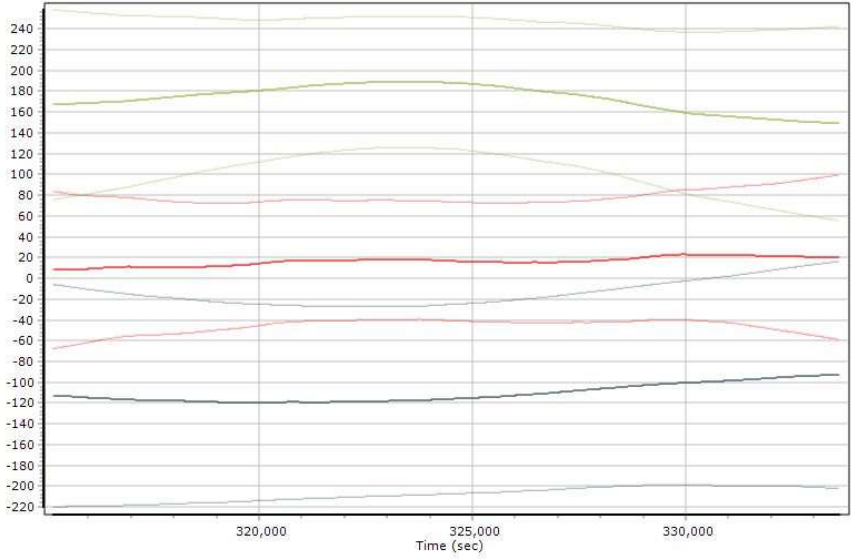
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



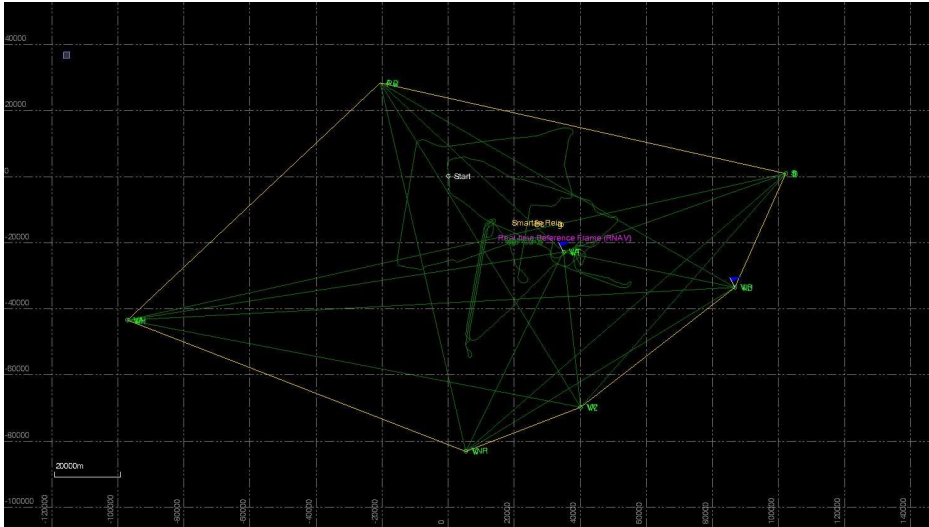


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



— x gyro scale error (ppm) — y gyro scale error (ppm) — z gyro scale error (ppm)

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Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
 - Export
- Camera
- LIDAR
- SAR

| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
|----------------------------|----------------------------------|
| X: 0.034 m | X: 0.000 deg |
| Y: 0.018 m | Y: 0.000 deg |
| Z: -0.155 m | Z: 0.000 deg |

| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
|-------------------------------------|---------------------------------------|
| X: -0.118 m | X: 0.000 deg |
| Y: -0.062 m | Y: 0.000 deg |
| Z: -0.952 m | Z: 0.000 deg |

Standard Deviation: <3cm 10cm 50cm 1m 10m

OK Cancel

Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
 - Export

Timing

Start: 562549.000

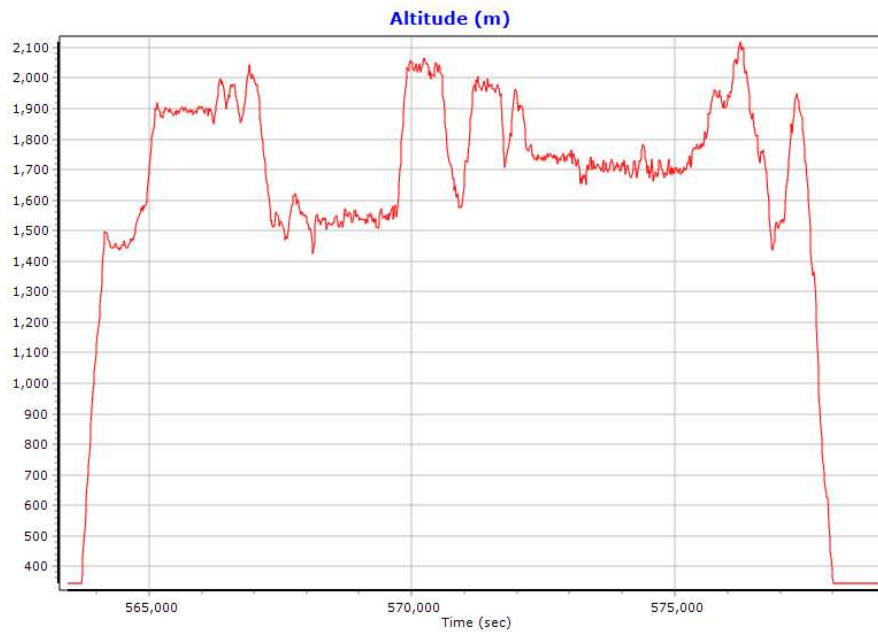
End: 578896.000

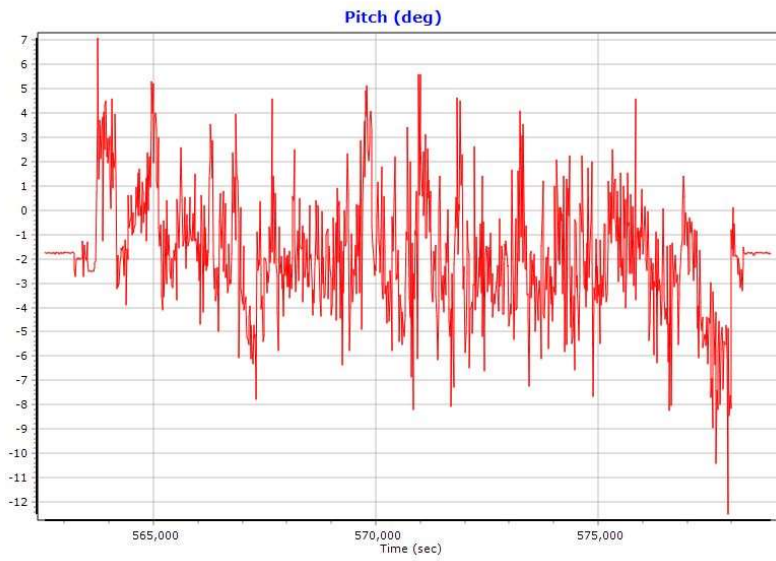
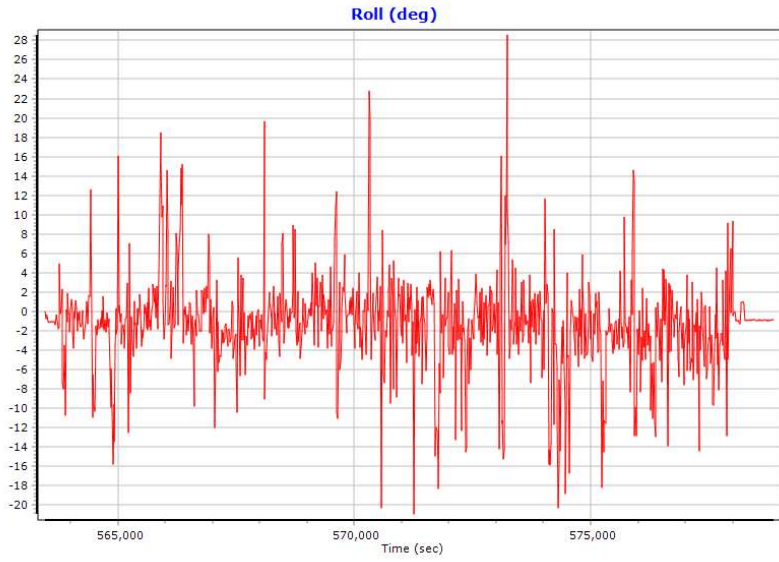
Entire time interval

Seconds of start week

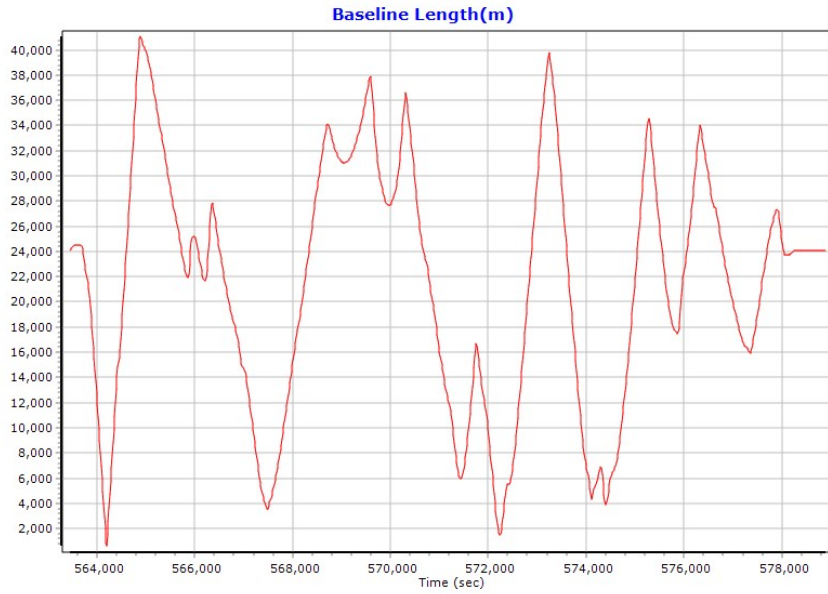
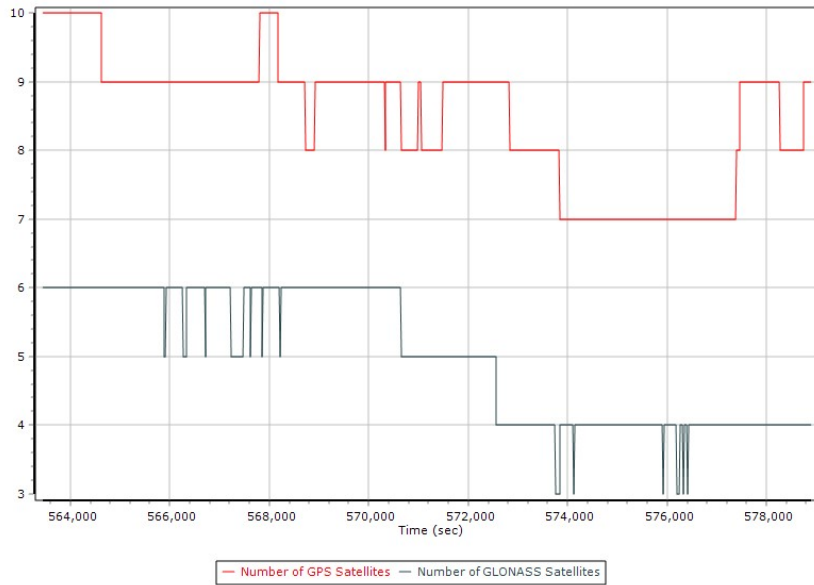
UTC Offset: 18.000

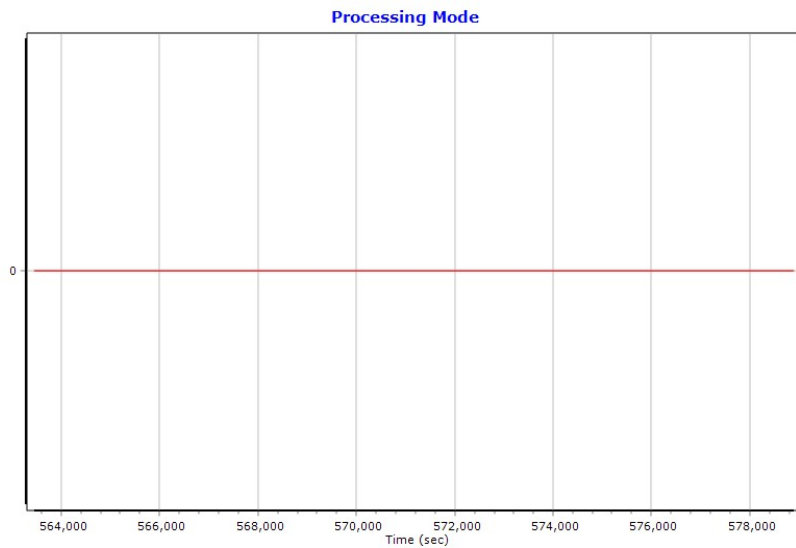
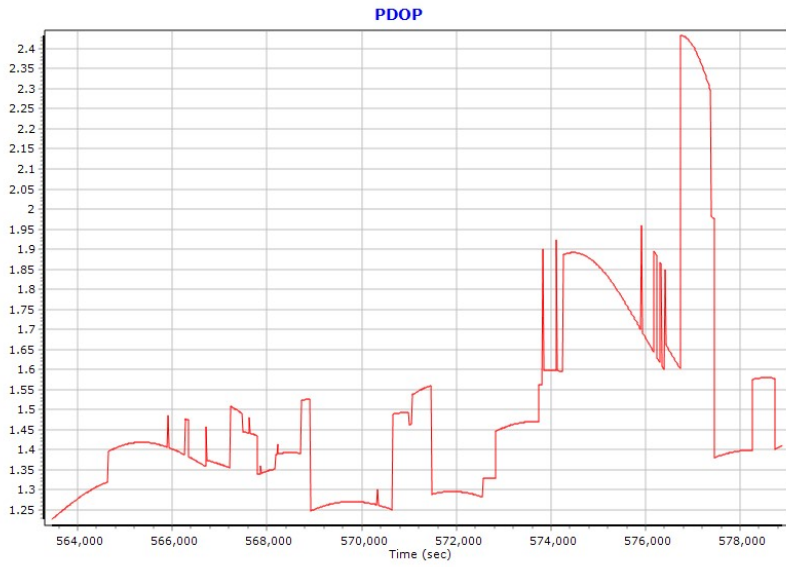
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |



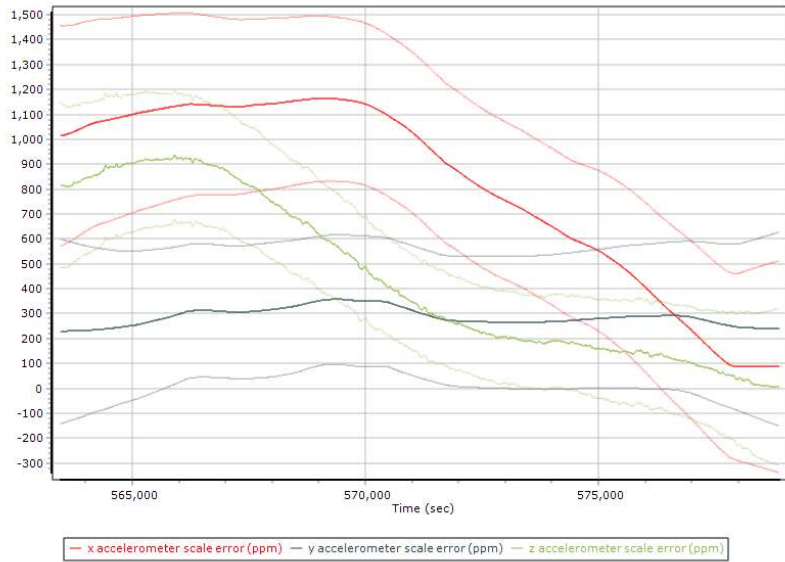
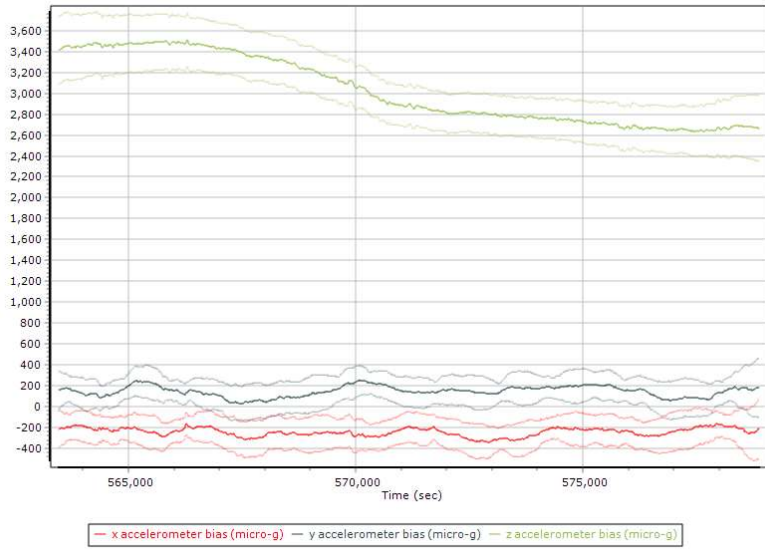


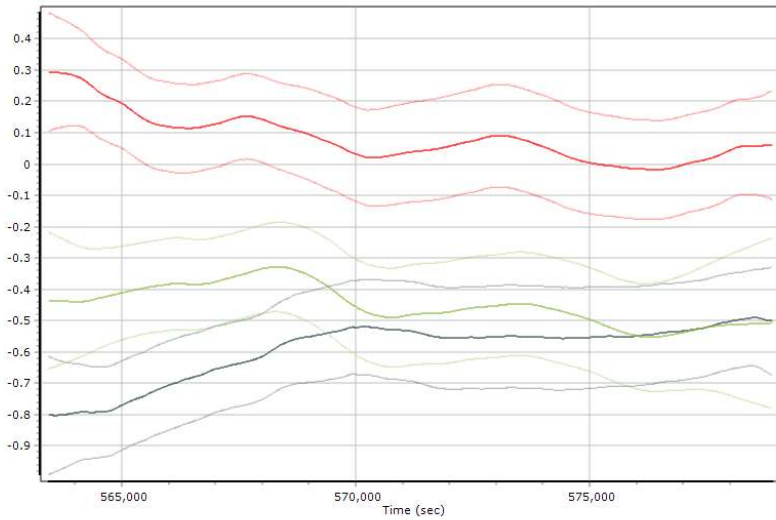




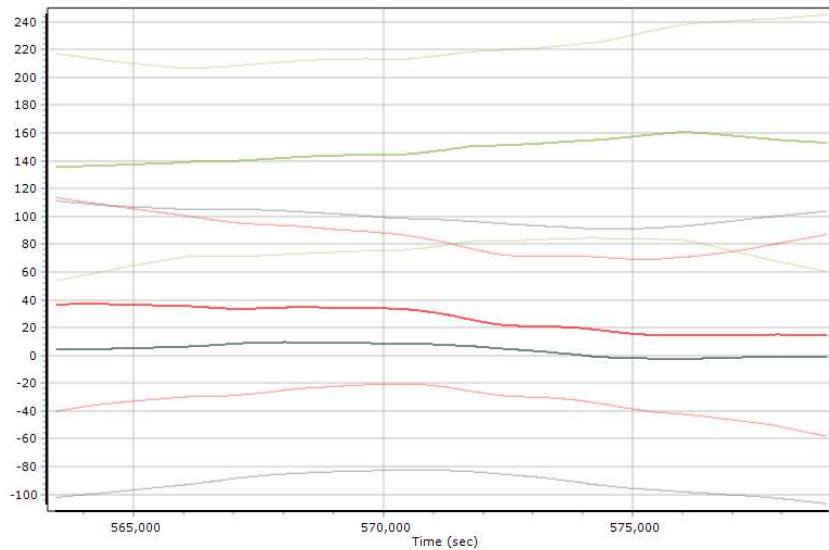


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



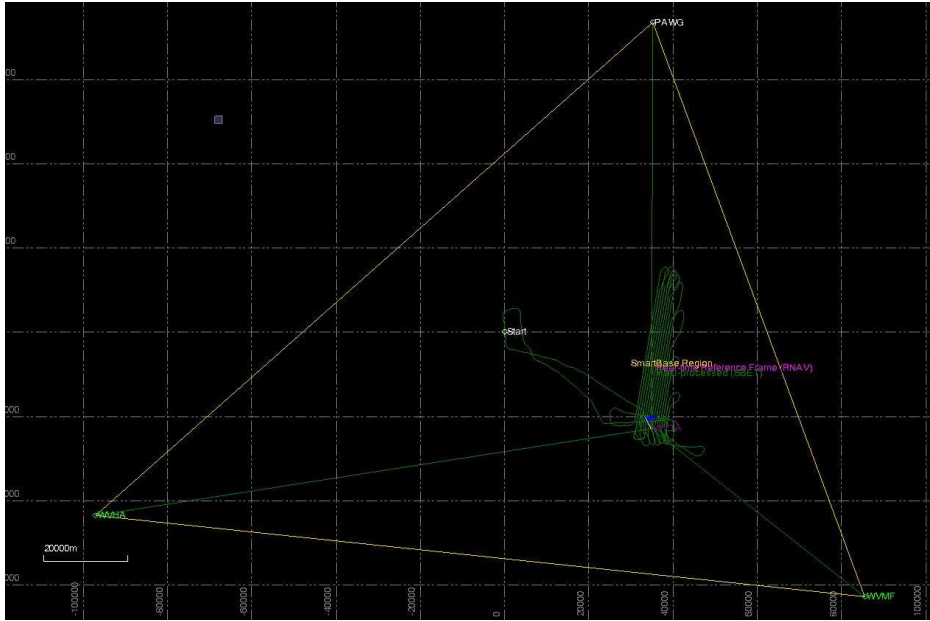


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



— x gyro scale error (ppm) — y gyro scale error (ppm) — z gyro scale error (ppm)

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| | |
|------------------------------------------------------|----------------------------------------------|
| Reference to IMU Lever Arm | Reference to IMU Mounting Angles |
| X: <input type="text" value="0.034 m"/> | X: <input type="text" value="0.000 deg"/> |
| Y: <input type="text" value="0.018 m"/> | Y: <input type="text" value="0.000 deg"/> |
| Z: <input type="text" value="-0.155 m"/> | Z: <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | Aircraft to Reference Mounting Angles |
| X: <input type="text" value="-0.118 m"/> | X: <input type="text" value="0.000 deg"/> |
| Y: <input type="text" value="-0.062 m"/> | Y: <input type="text" value="0.000 deg"/> |
| Z: <input type="text" value="-0.952 m"/> | Z: <input type="text" value="0.000 deg"/> |
| Standard Deviation: <input type="text" value="3cm"/> | |
| <3cm 10cm 50cm 1m 10m | |

Timing

Start: 130647.000

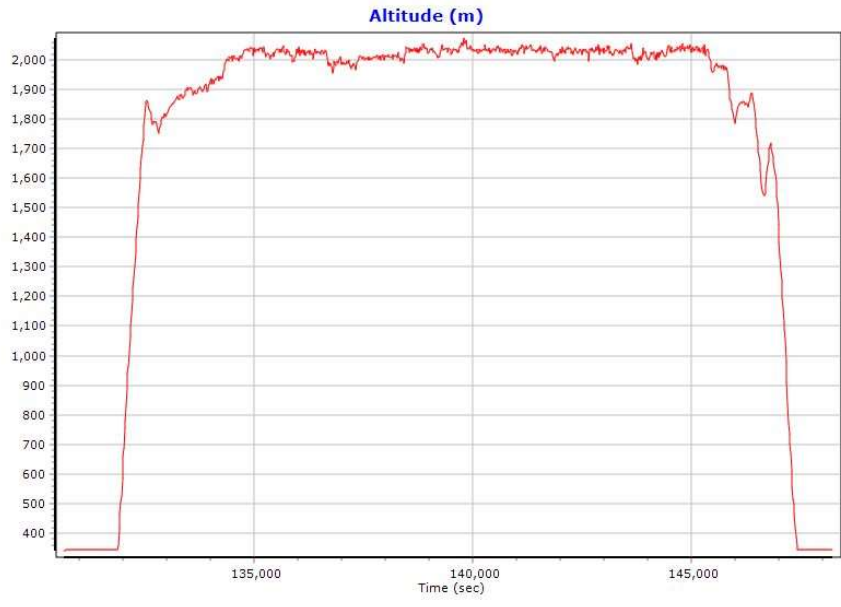
End: 148222.000

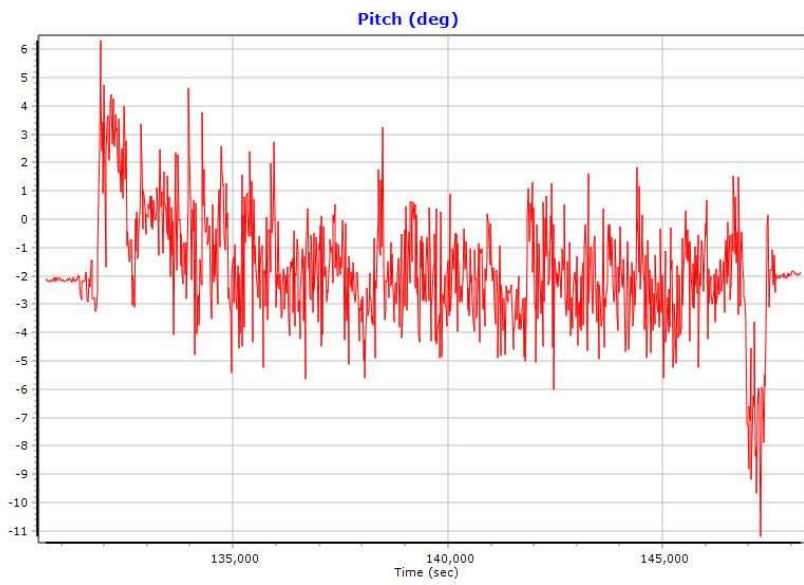
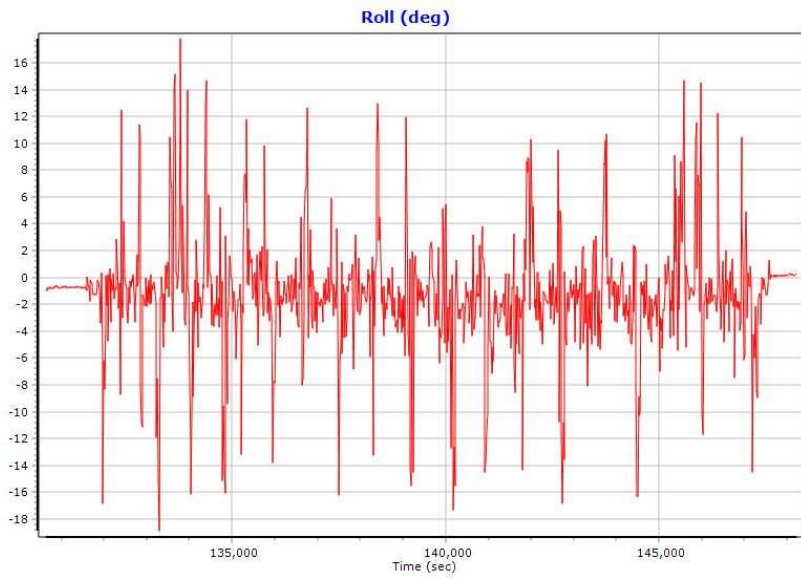
Entire time interval

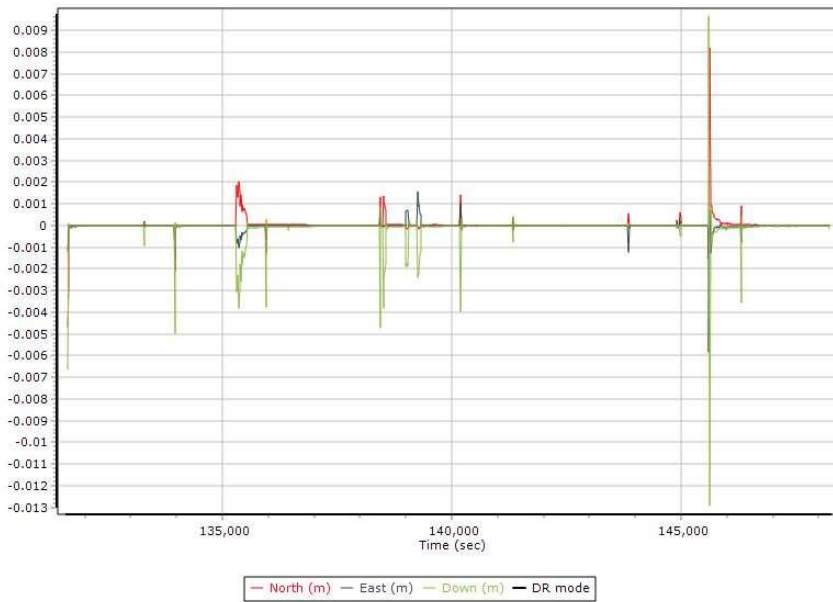
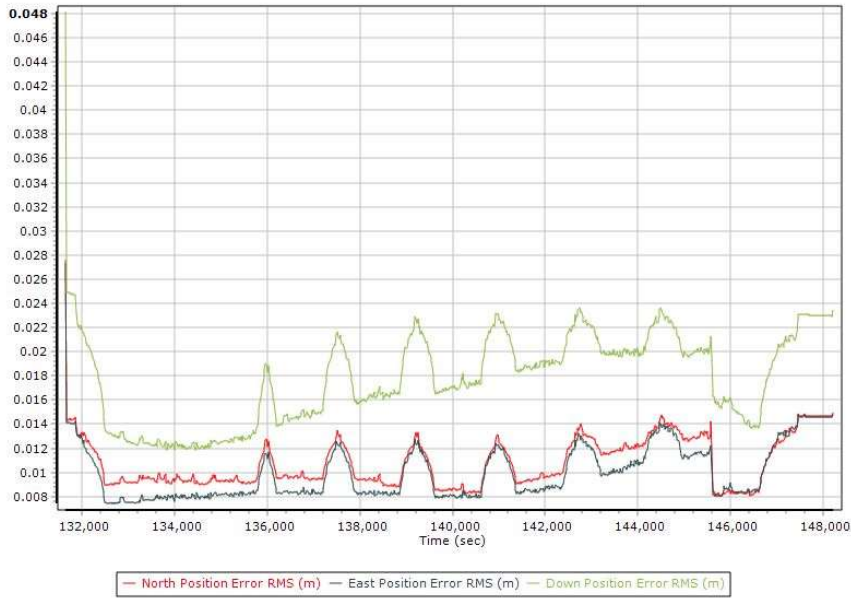
Seconds of start week

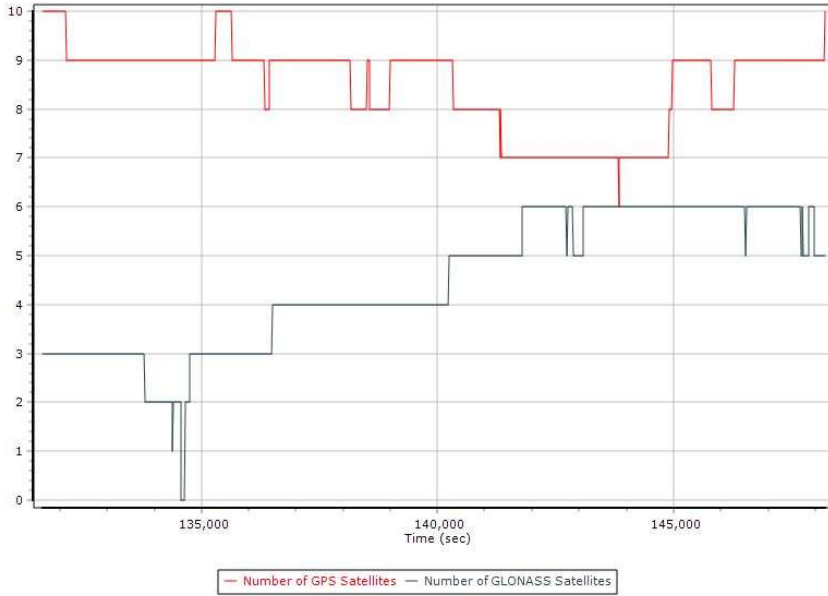
UTC Offset: 18.000

| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |

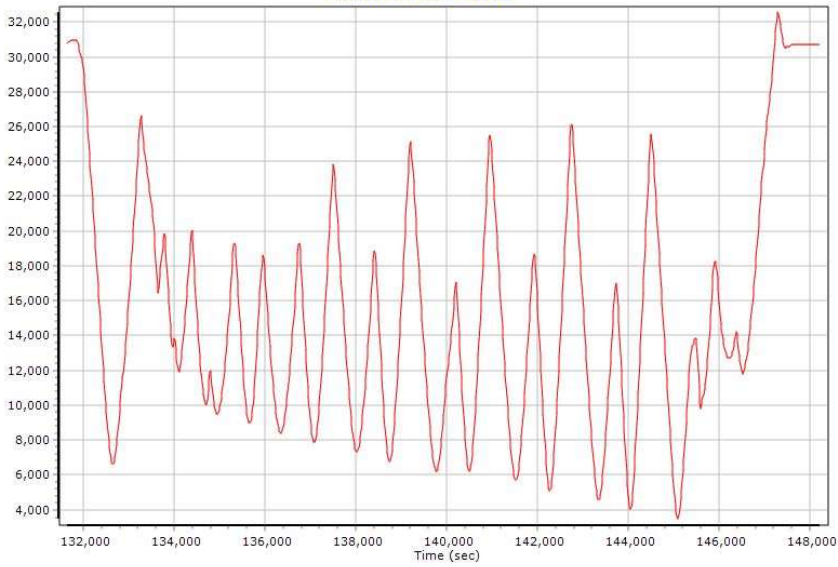




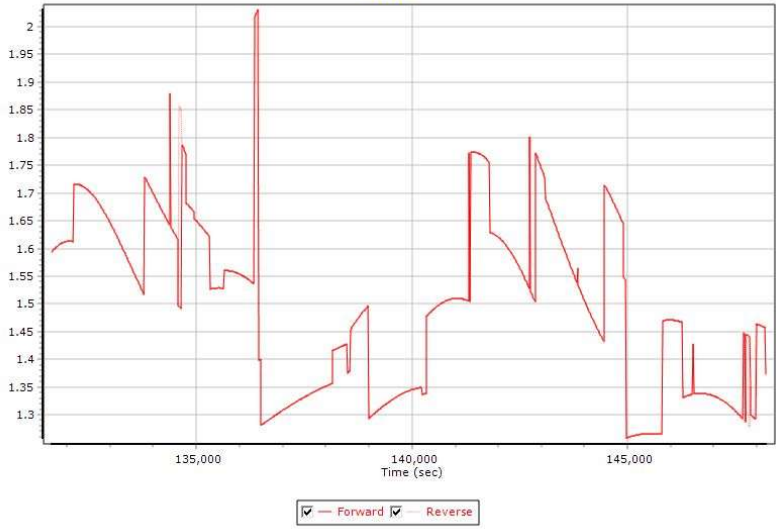




Baseline Length(m)

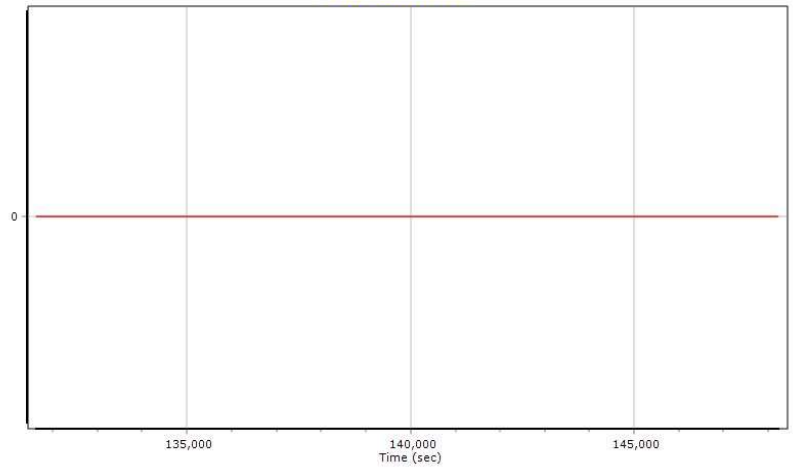


PDOP



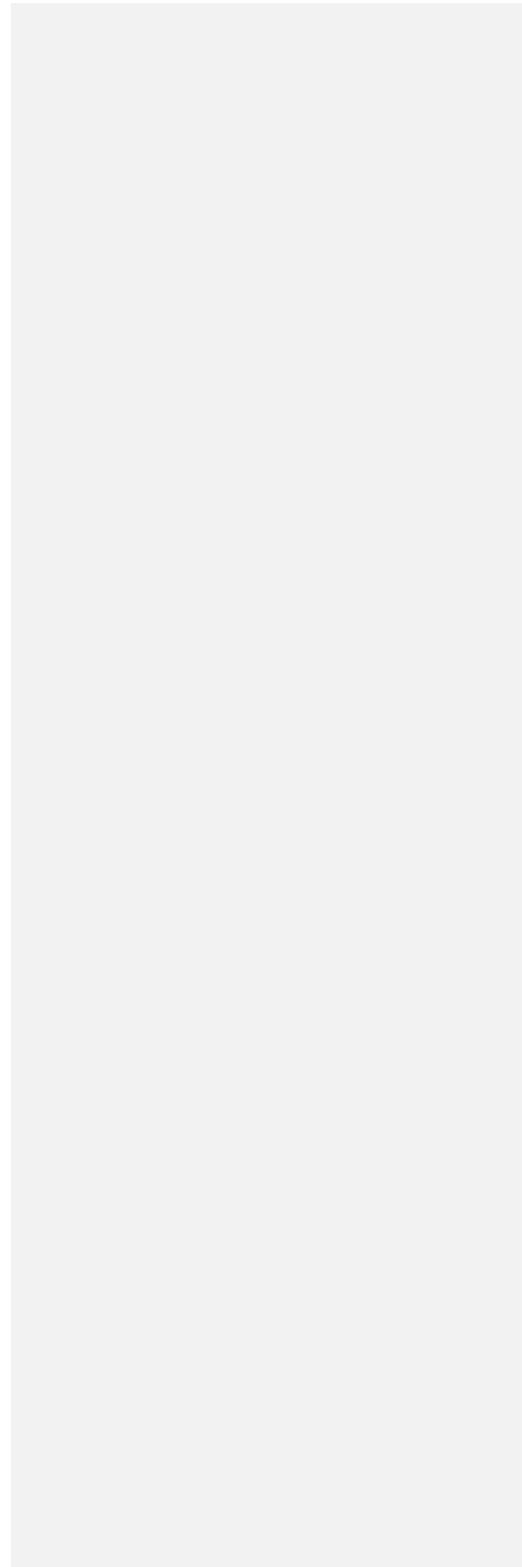
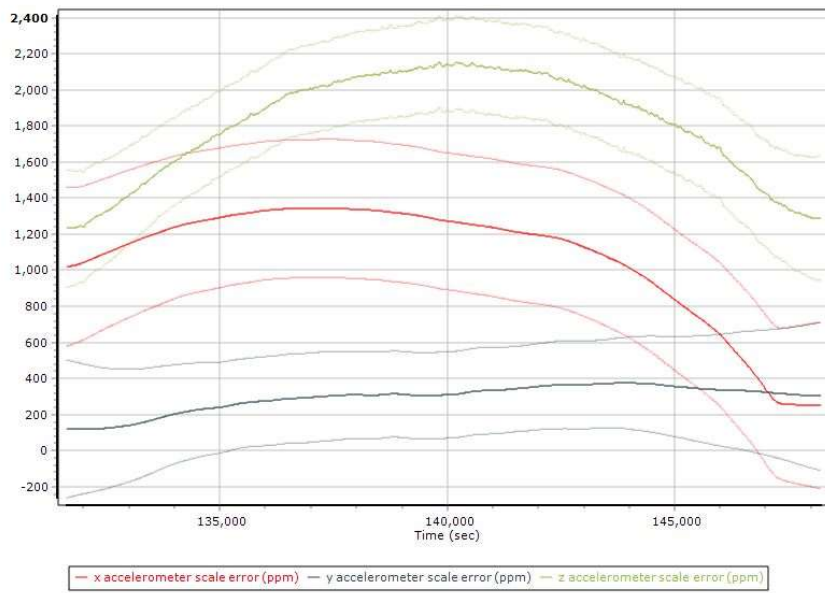
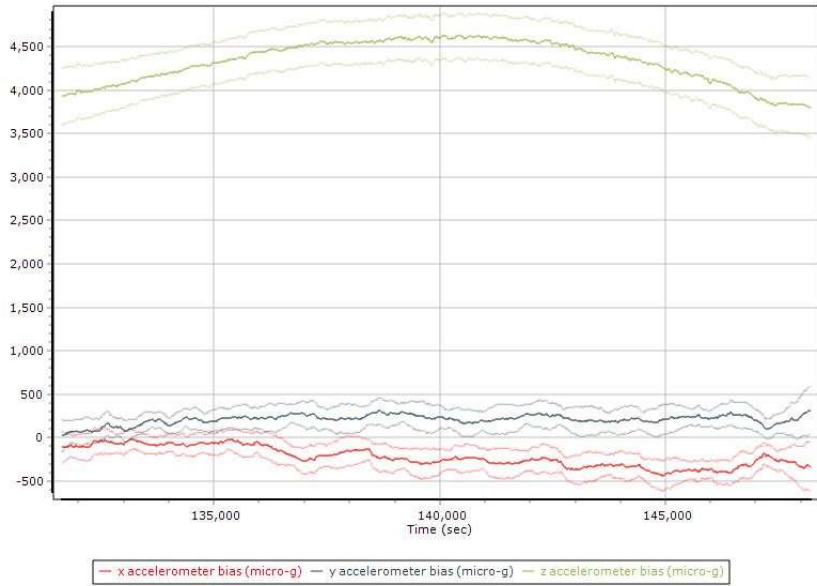
Forward Reverse

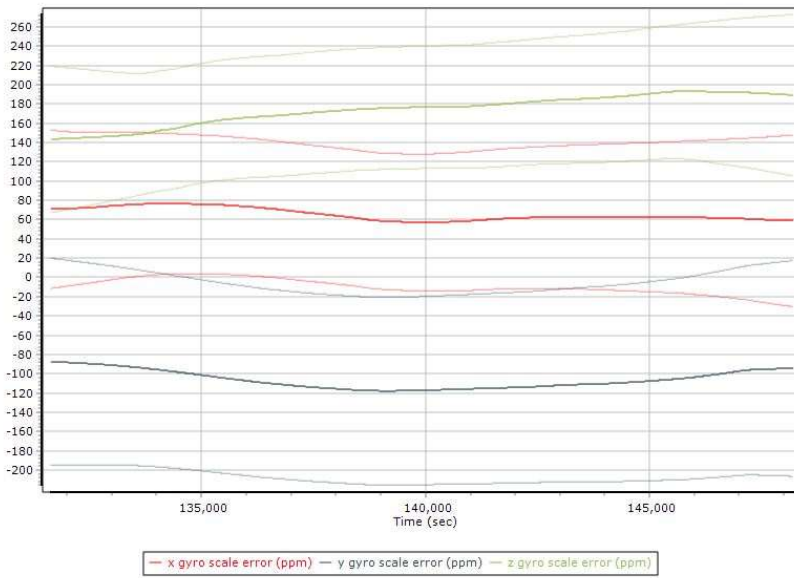
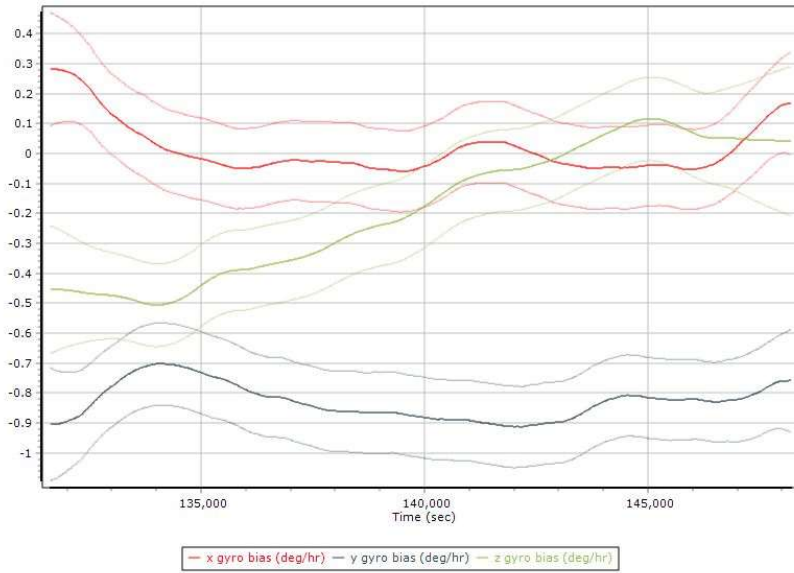
Processing Mode



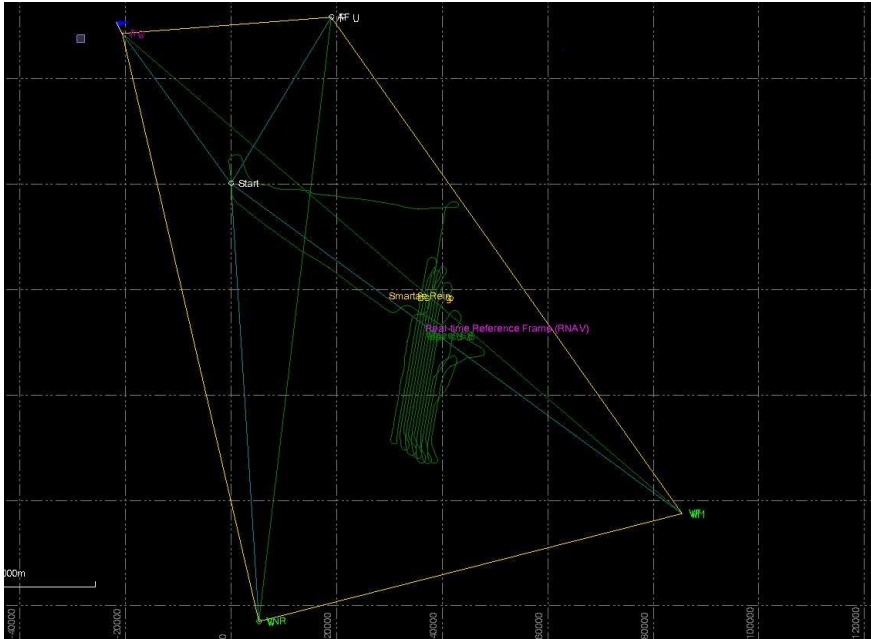
Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR





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| | | | |
|--------------------------------------------|---------------------------------------|----------------------------------------------|----------------------------------------|
| Reference to IMU Lever Arm | | Reference to IMU Mounting Angles | |
| X | <input type="text" value="0.034 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="0.018 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.155 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Reference to Primary GNSS Lever Arm | | Aircraft to Reference Mounting Angles | |
| X | <input type="text" value="-0.118 m"/> | X | <input type="text" value="0.000 deg"/> |
| Y | <input type="text" value="-0.062 m"/> | Y | <input type="text" value="0.000 deg"/> |
| Z | <input type="text" value="-0.952 m"/> | Z | <input type="text" value="0.000 deg"/> |
| Standard Deviation | | | |
| <input type="range" value="3cm"/> | | | |
| <p><3cm 10cm 50cm 1m 10m</p> | | | |

Timing

Start: 151541.000

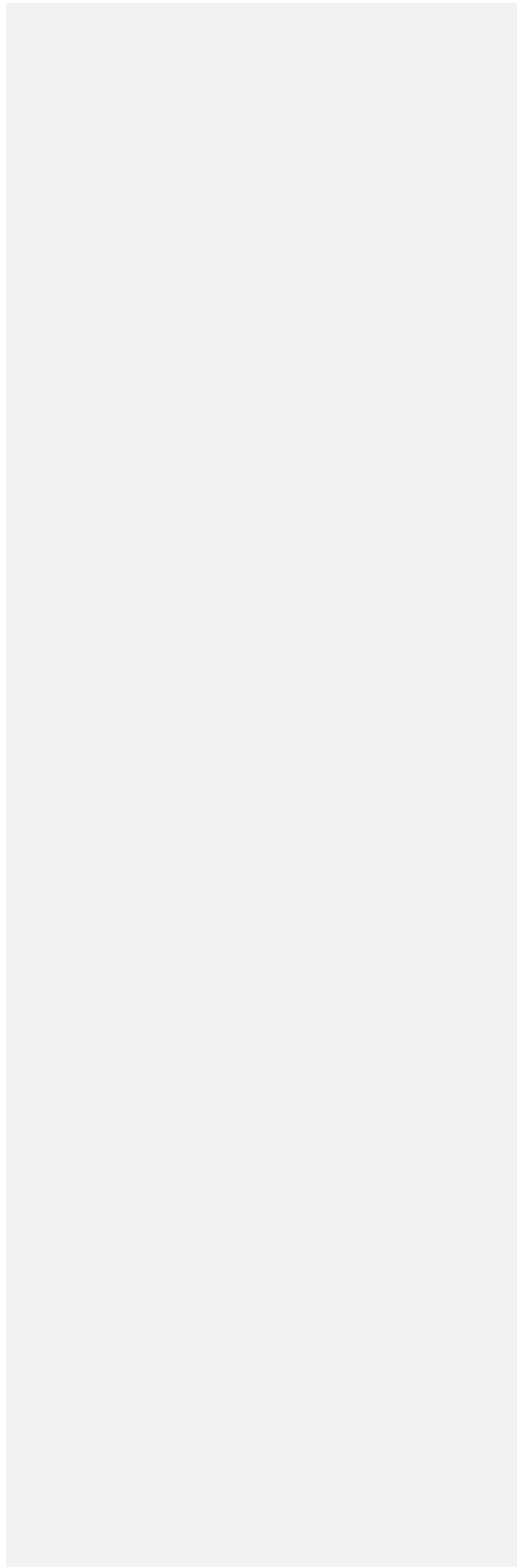
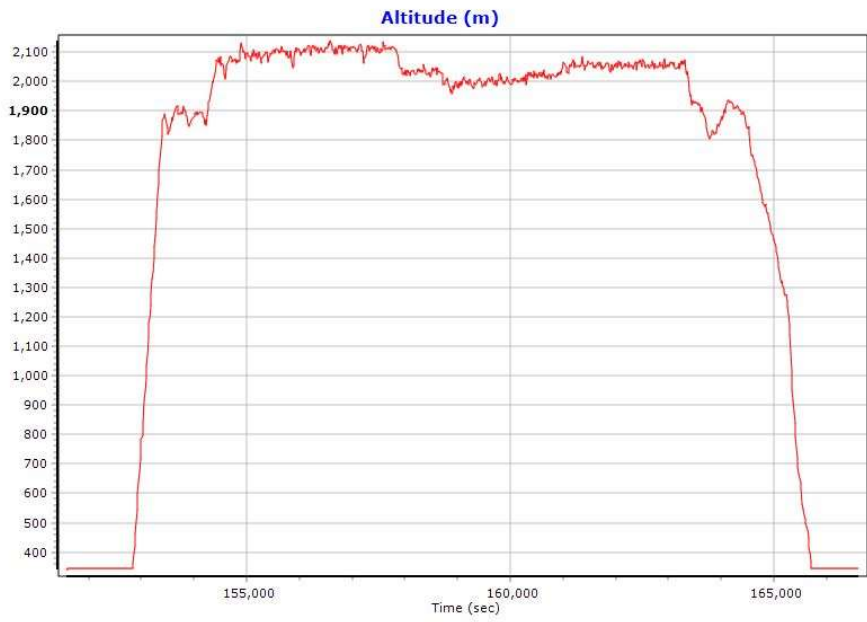
End: 166615.000

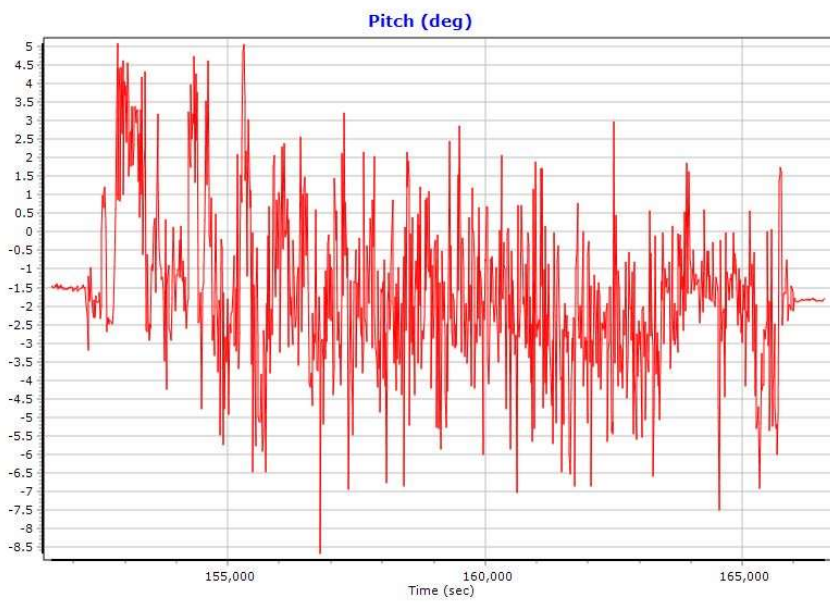
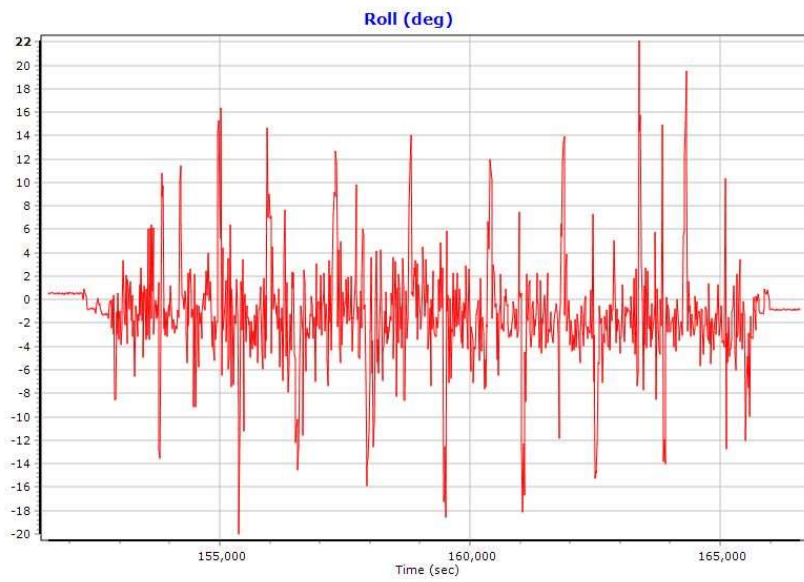
Entire time interval

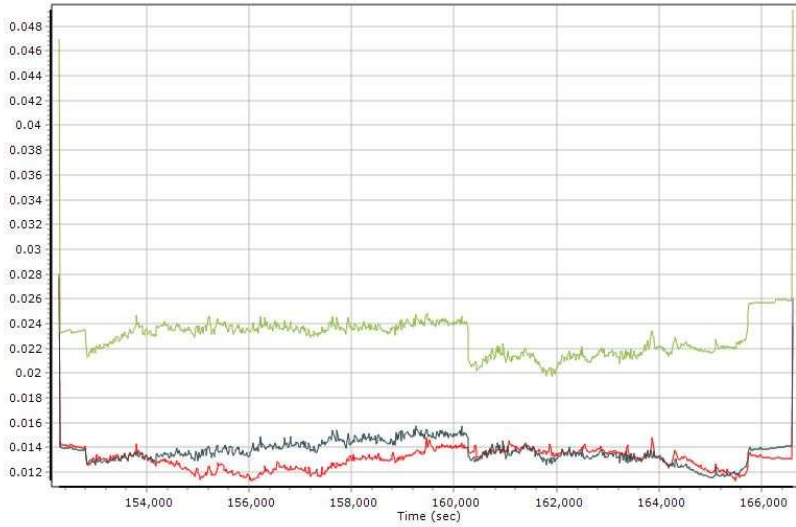
Seconds of start week

UTC Offset: 18.000

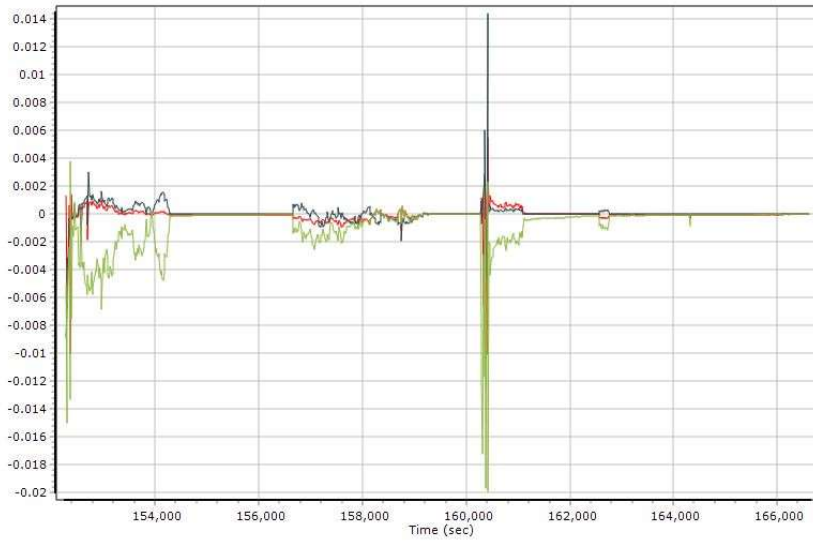
| Data | Incr. (sec) |
|---------------|-------------|
| Output Record | 0.005000 |
| IMU | 0.005000 |
| Primary GNSS | 1.000000 |



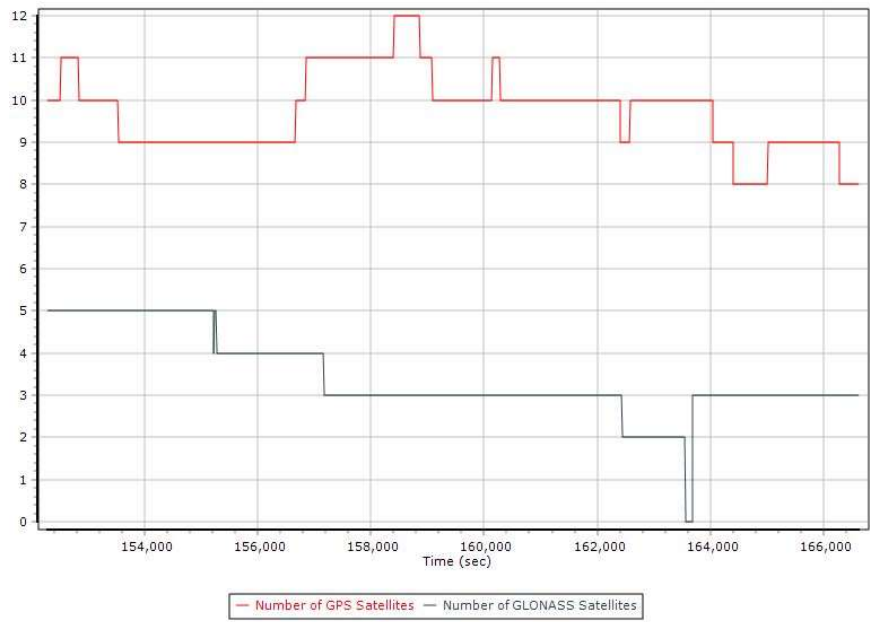




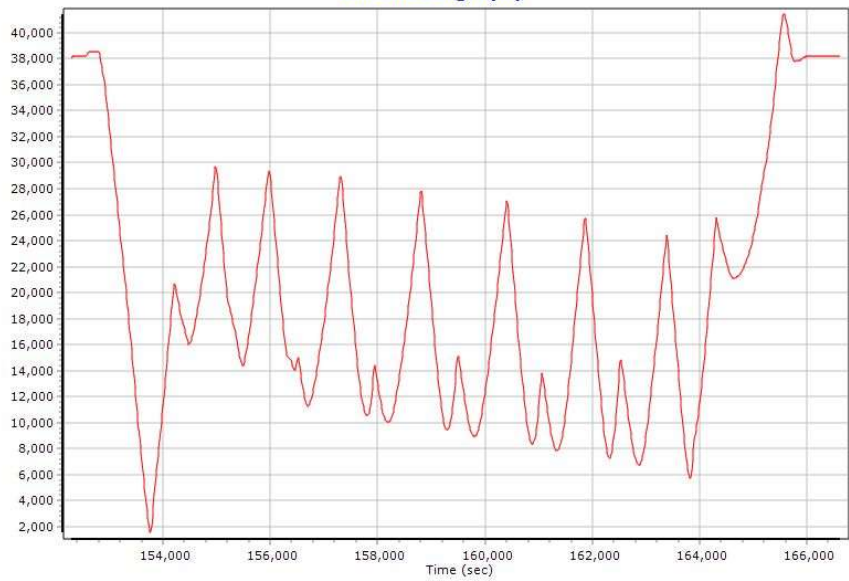
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



— North (m) — East (m) — Down (m) — DR mode



Baseline Length(m)

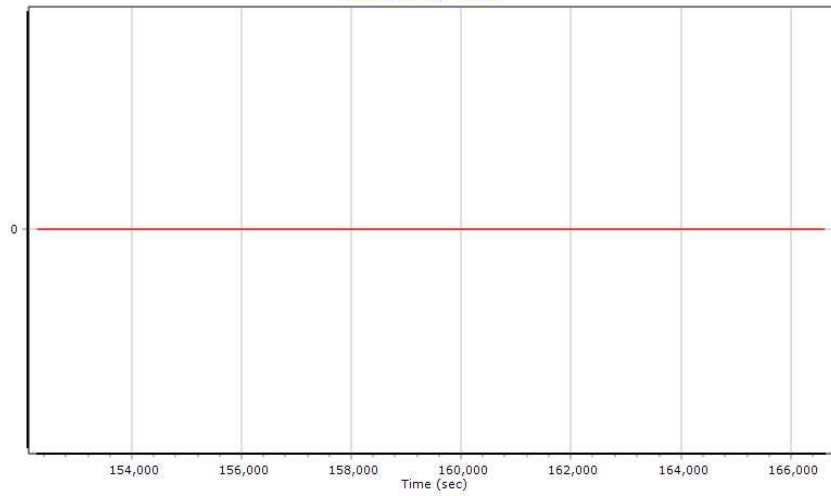


PDOP



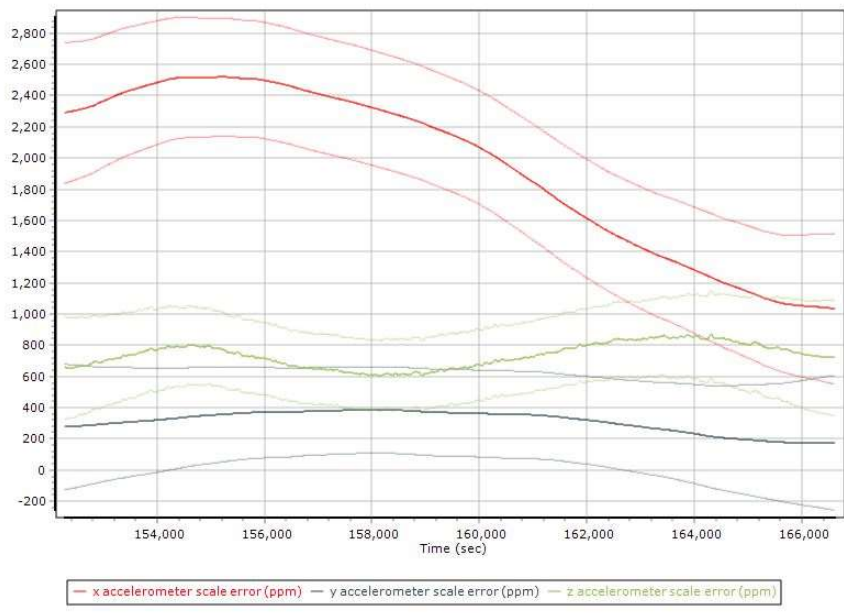
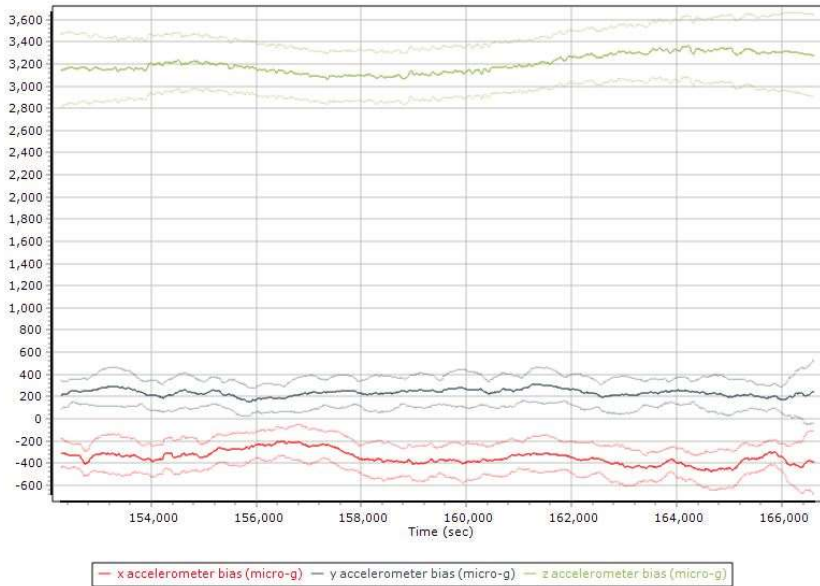
Forward Reverse

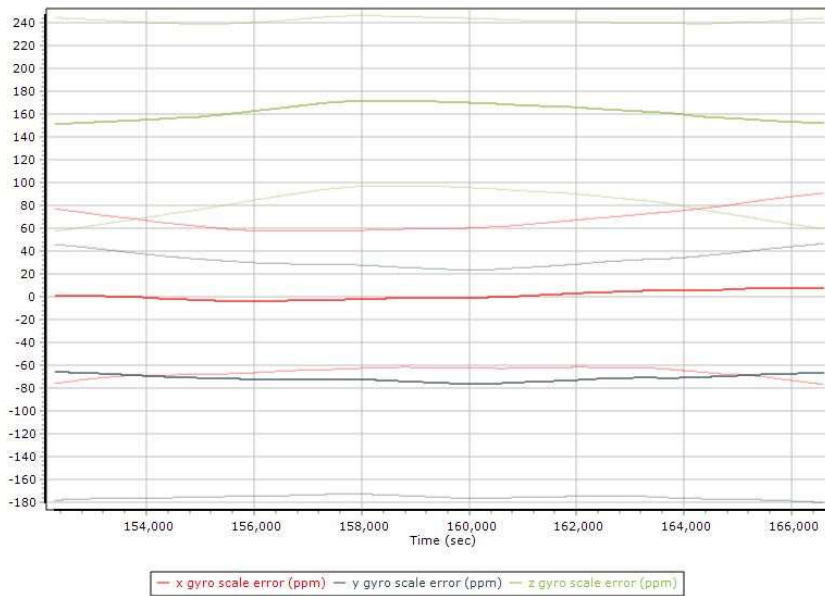
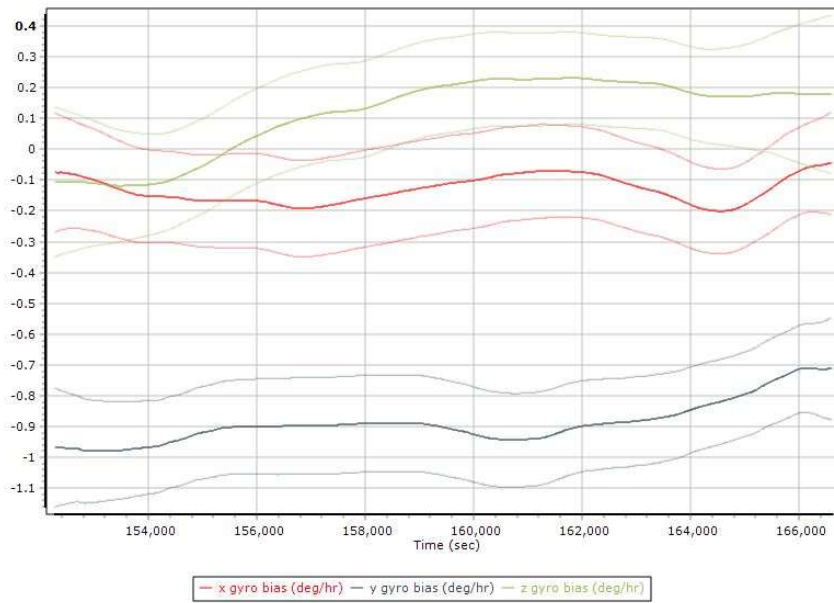
Processing Mode



Forward Reverse

0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR





End

