General Information

Mission Information

Project name	19-058_111919
Processing date	2019-11-25 21:39:42
Mission date	2019-11-19 15:35:09
Mission duration	04:29:59.000
Processing mode	IN-Fusion Trimble RTX Nav

Rover Hardware Information

Product	POS AV 610 VER6 HW2.5-12
Serial number	S/N6675
IMU type	57
Receiver type	BD982
Antenna type	AV39

Project File List

Rover Data Files

File name	File type
191119_153508_POSAV610-6675.raw	POS Data

Input Files

File Name	File type
Ephm3230.19g	GLONASS Broadcast Ephemeris
Ephm3230.19n	GPS Broadcast Ephemeris

Output Files

Filename	File type
sbet_19-058_111919.out	SBET Trajectory File

Rover Data Summary

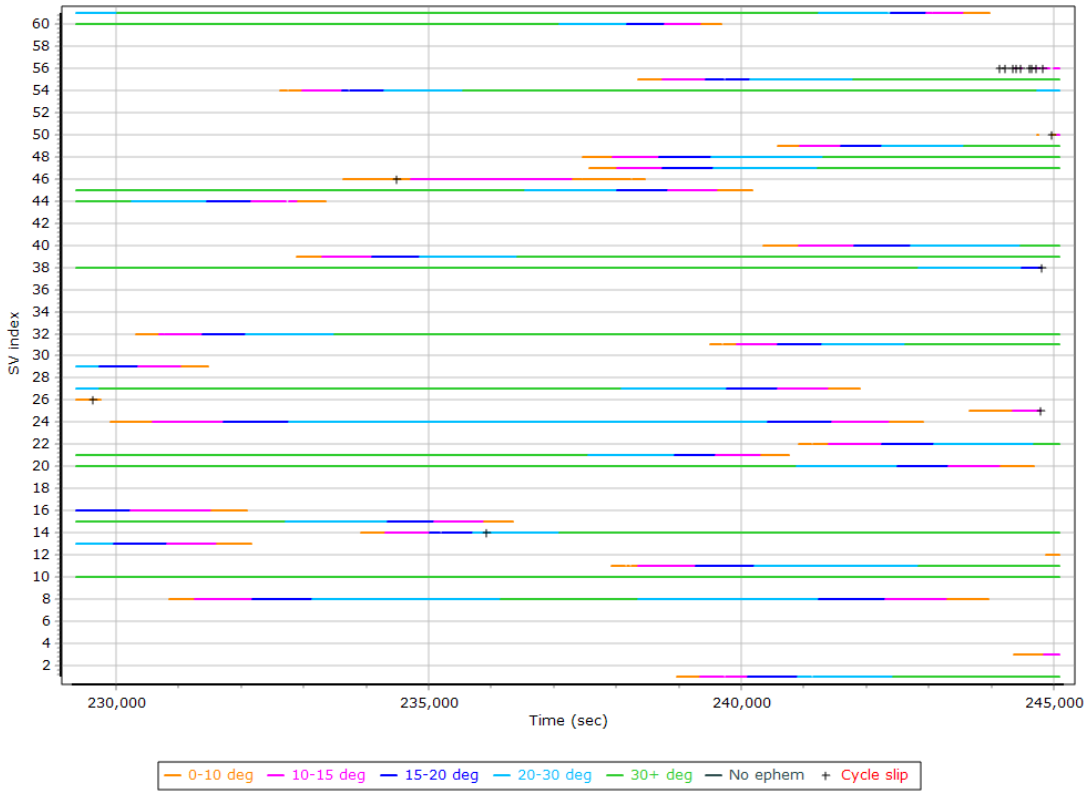
First raw data file	191119_153508_POSAV610-6675.raw		
Last raw data file	191119_153508_POSAV610-6675.raw		
Start GPS week	2080		
Start time	228908.947 (11/19/2019 15:34:50)		
End time	245108.664 (11/19/2019 20:04:50)		
Start of fine alignment	229306.046 (11/19/2019 15:41:28)		
Available subsystems	Primary GNSS, Gimbal, IMU		
POS Event Input	None		
Correction data	Trimble RTX		
IMU Installation Lever Arms & Mounting Angles			
Gimbal to IMU lever arm [m]	0.000	0.000	0.000
Gimbal to IMU mounting angles [deg]	0.000	0.000	0.000
Gimbal to Primary GNSS lever arm [m]	-0.233	-0.013	-0.922
Gimbal to Primary GNSS lever arm std dev [m]	-1.000		
Aircraft to Reference mounting angles [deg]	0.000	0.000	0.000

Raw Data QC

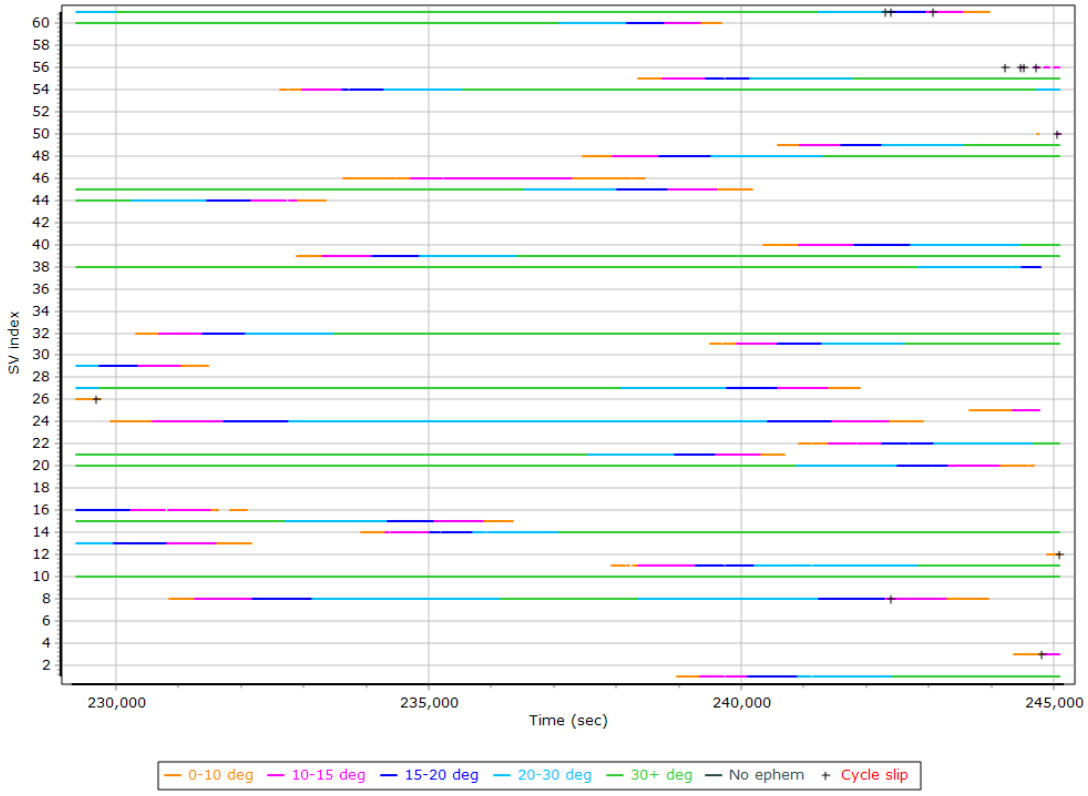
Raw IMU Import QC Summary

IMU data input file	imu_Mission 1.dat
IMU data check log file	imudt_19-058_111919.log
IMU Records Processed	3239279
Termination Status	Normal
IMU Anomalies	0

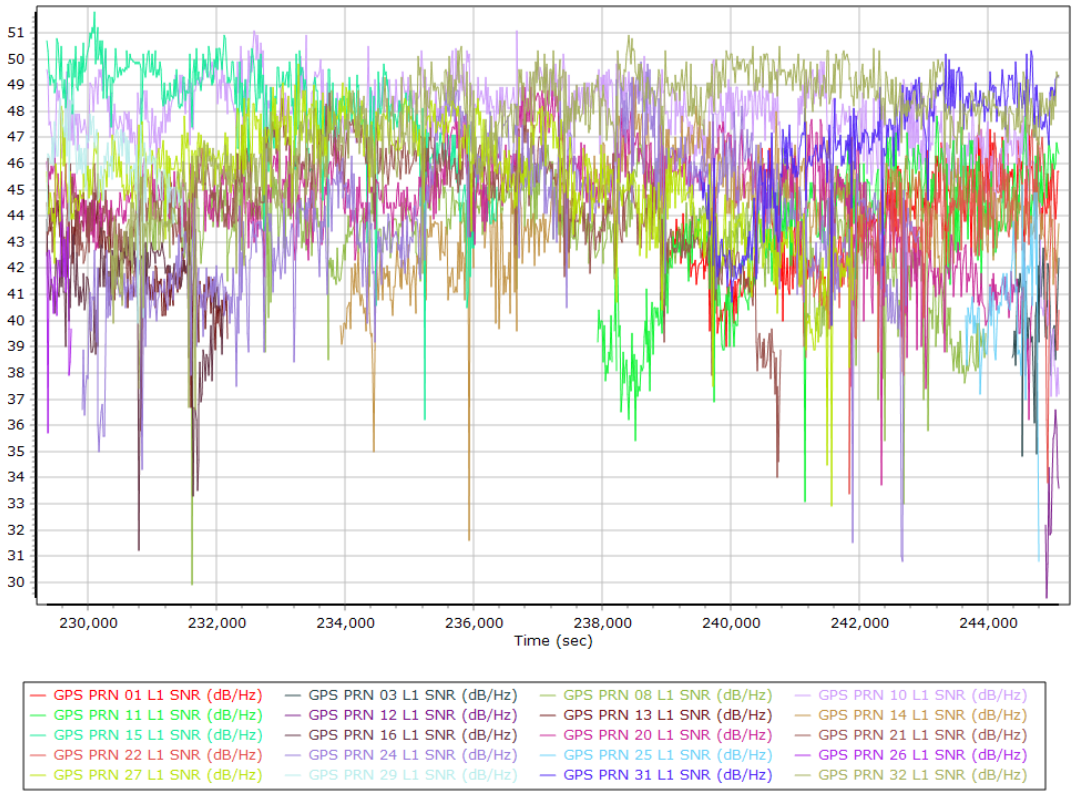
L1 Satellite Lock/Elevation



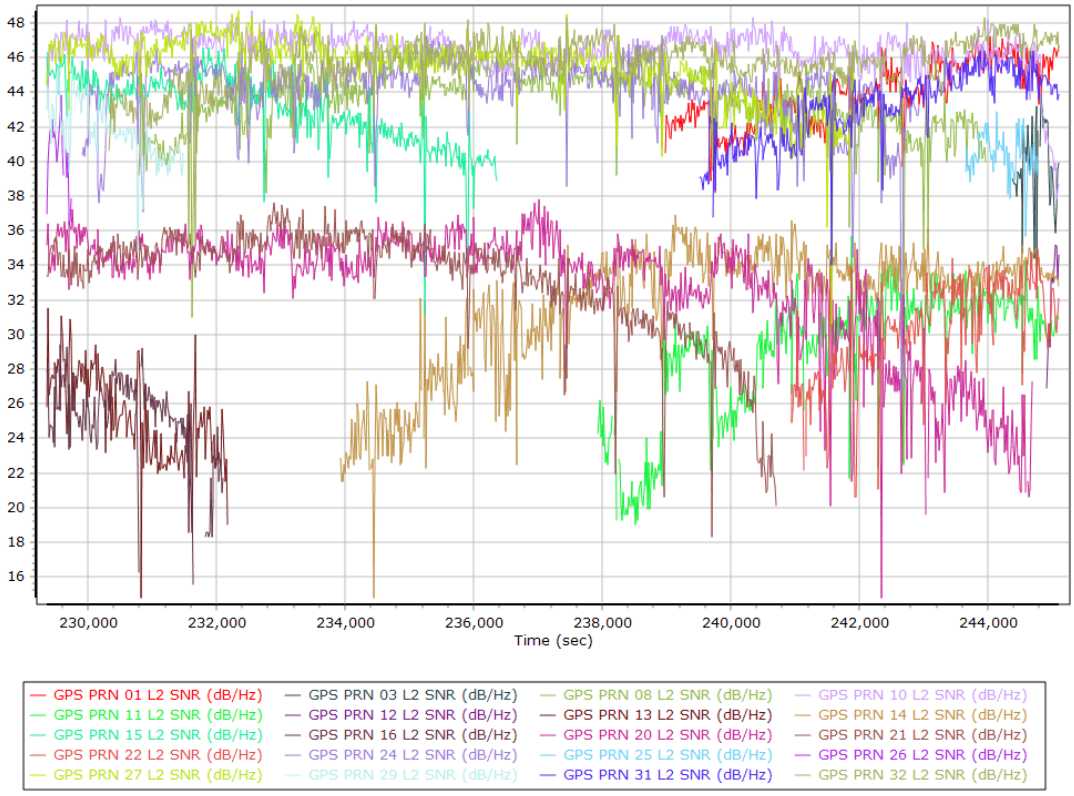
L2 Satellite Lock/Elevation



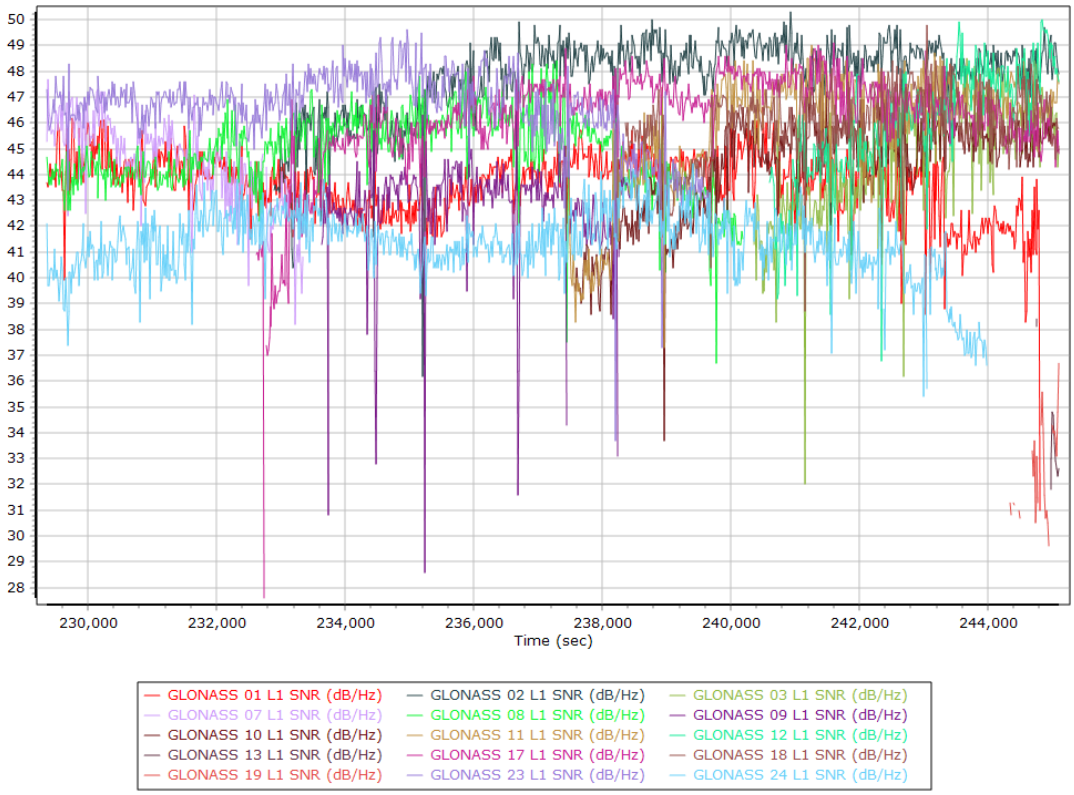
GPS L1 SNR



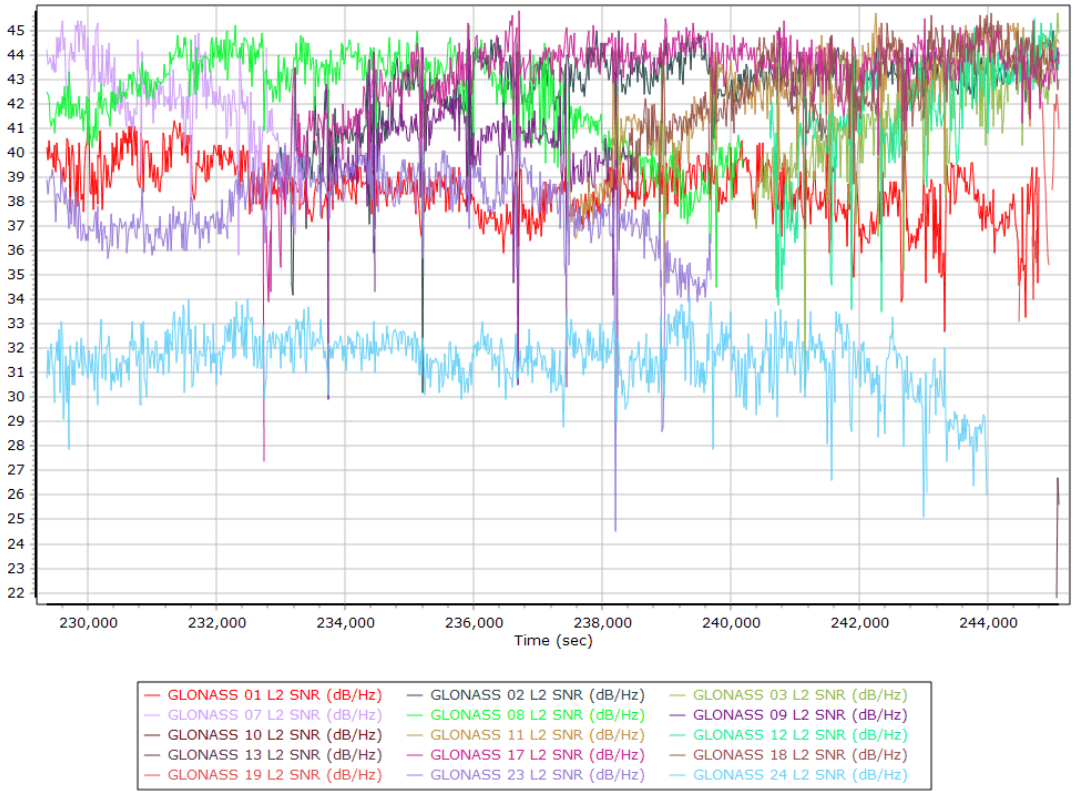
GPS L2 SNR



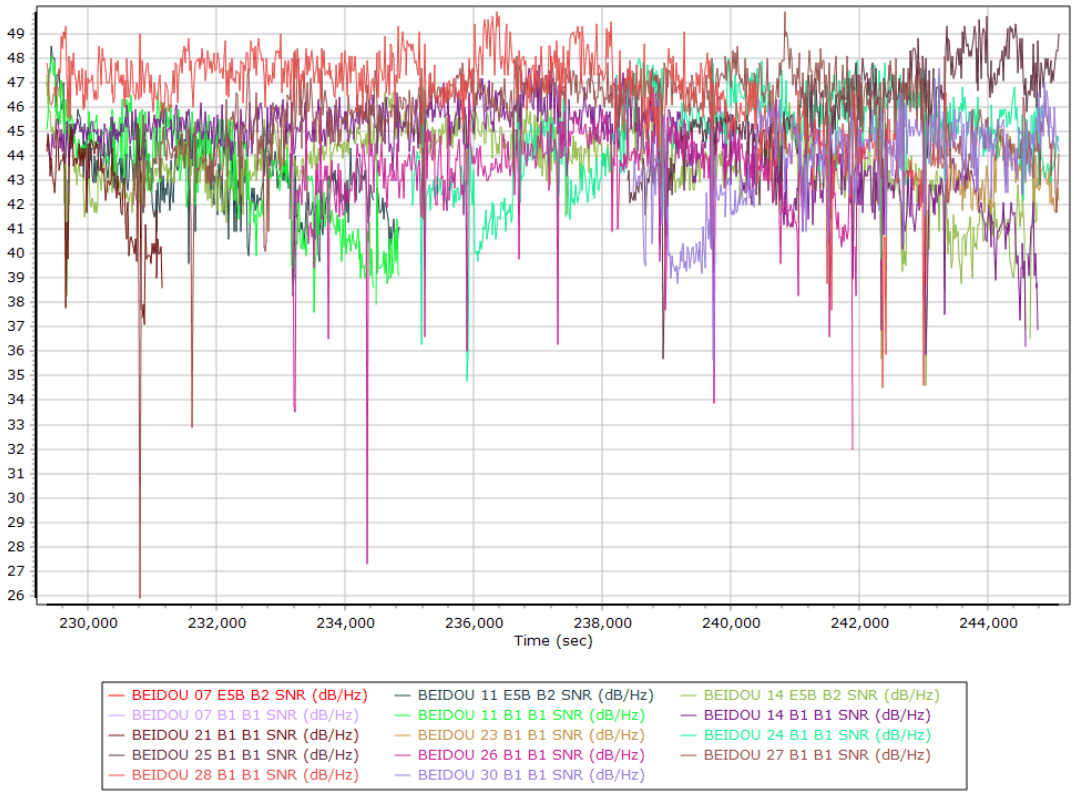
GLONASS L1 SNR



GLONASS L2 SNR

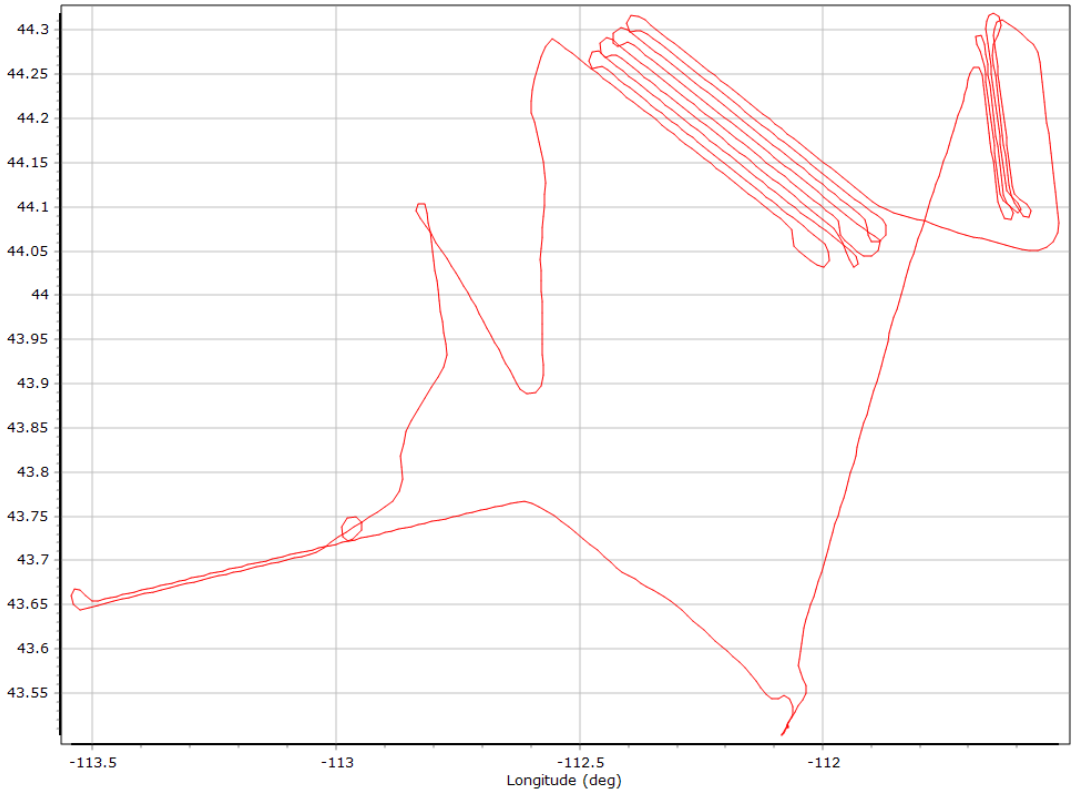


BEIDOU SNR

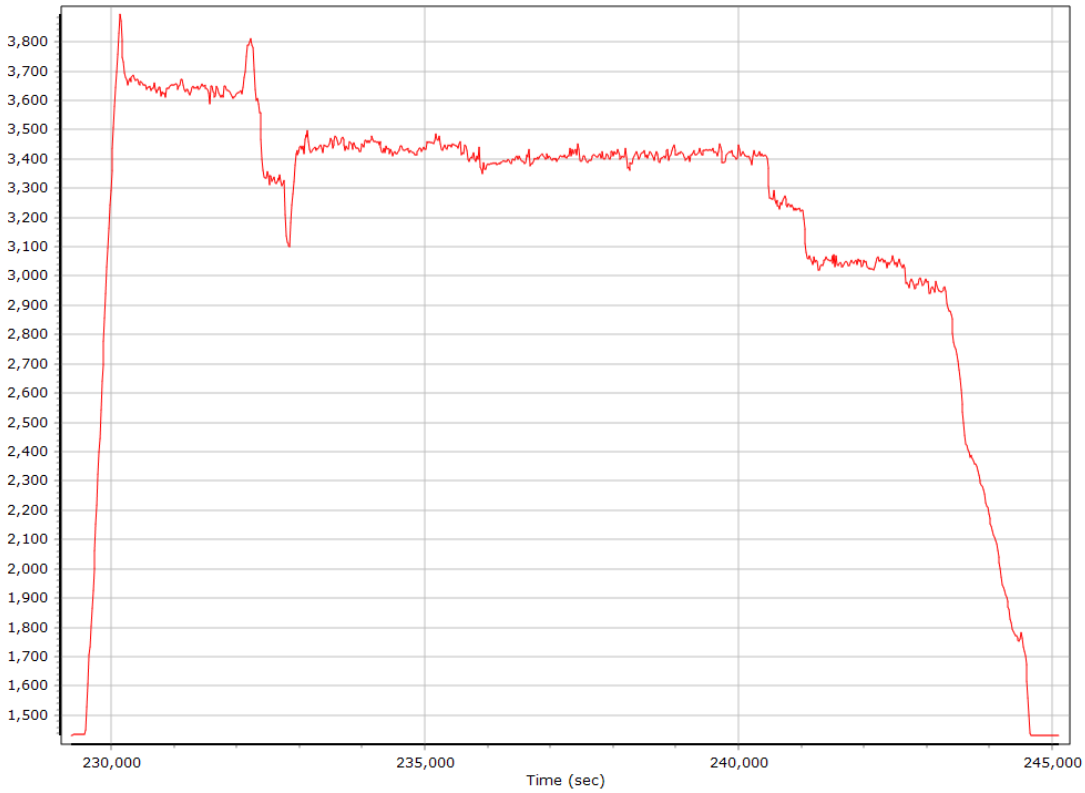


Trajectory Information

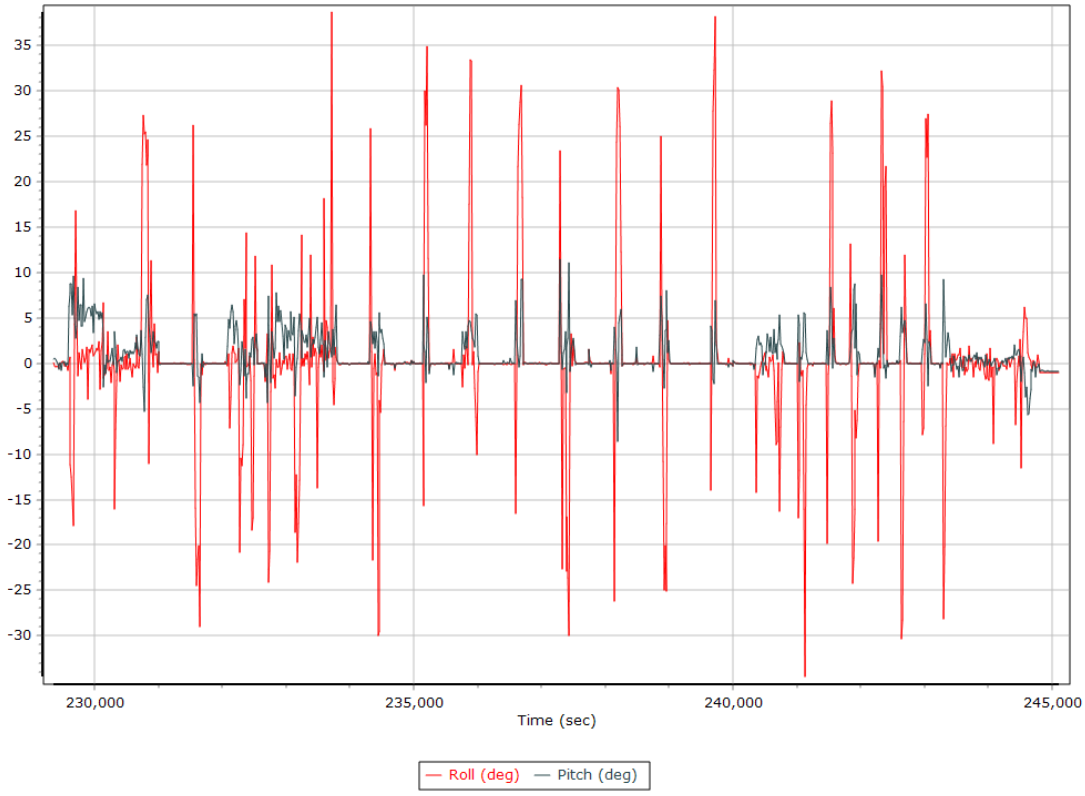
Top View



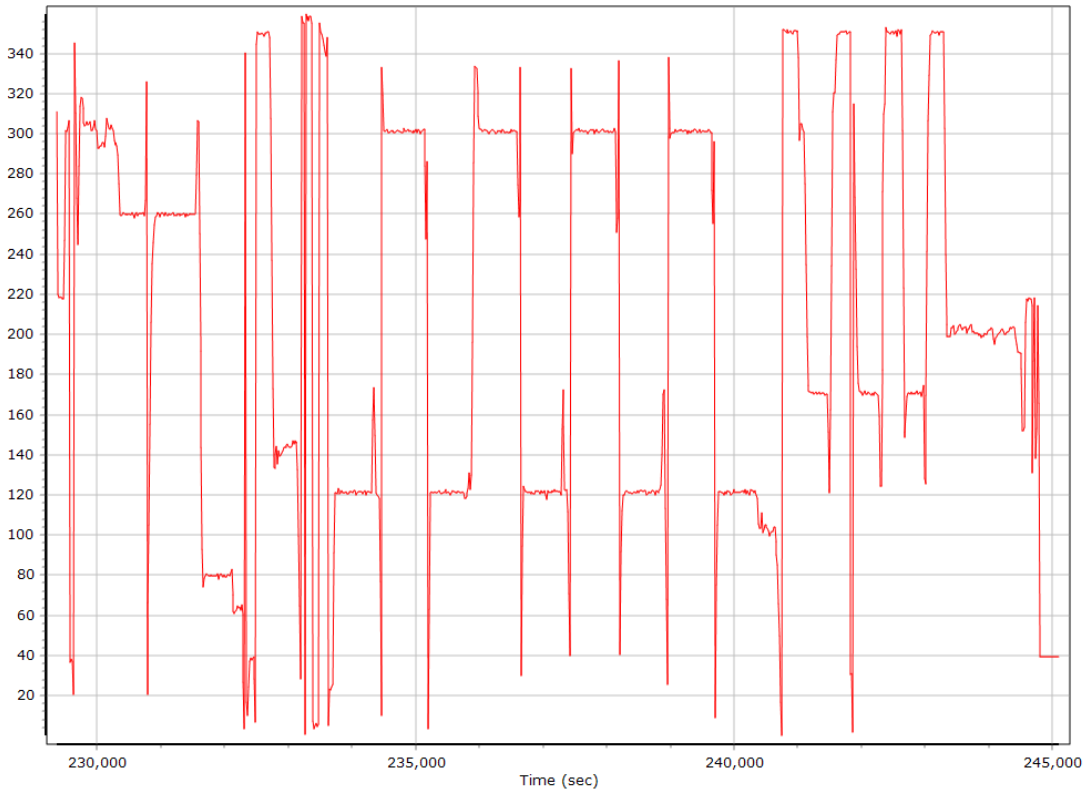
Altitude



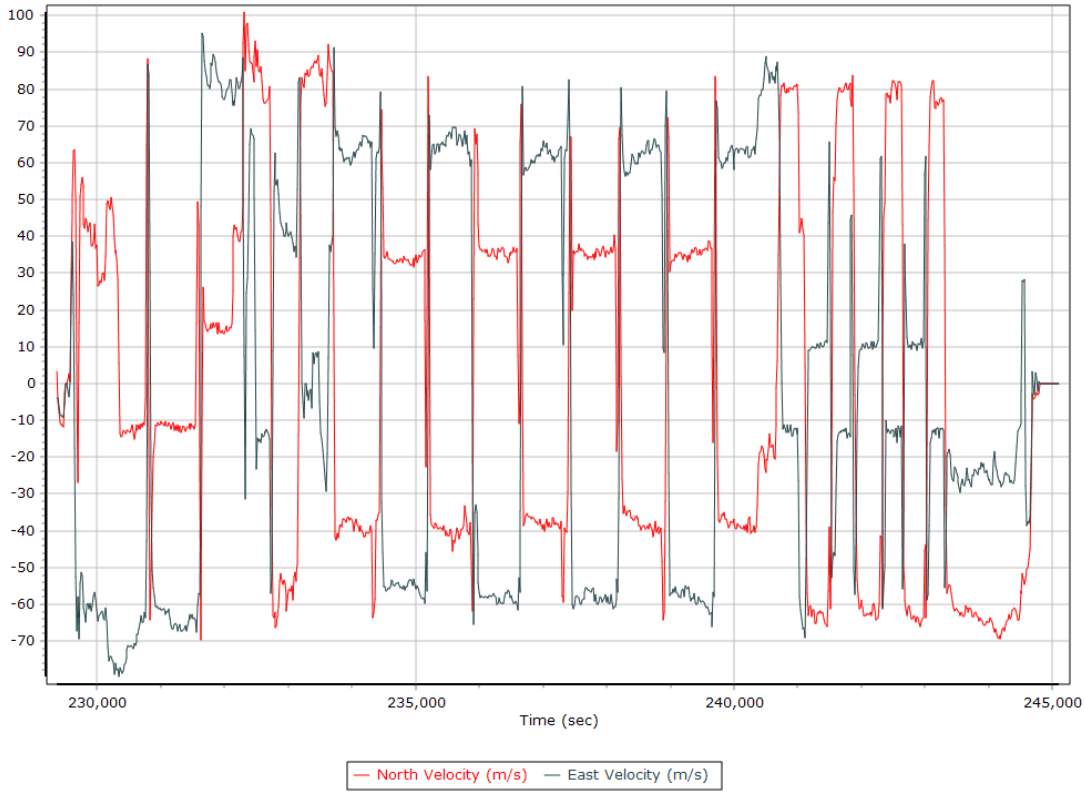
Roll/Pitch



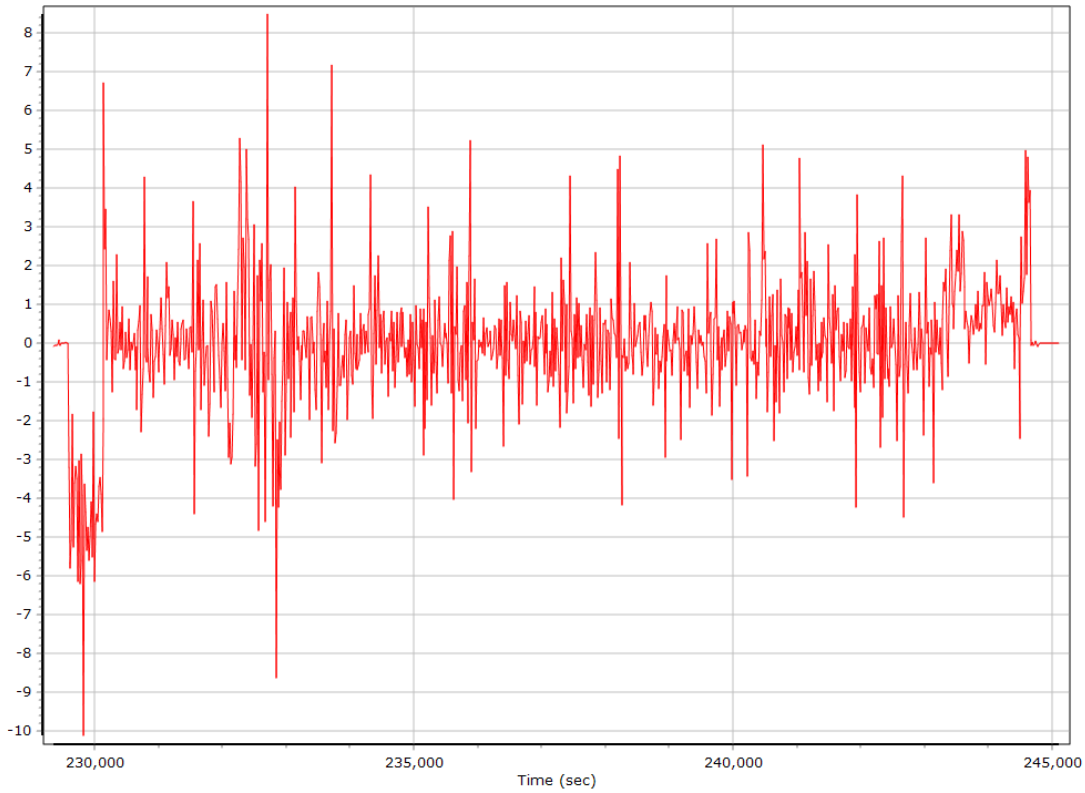
Heading



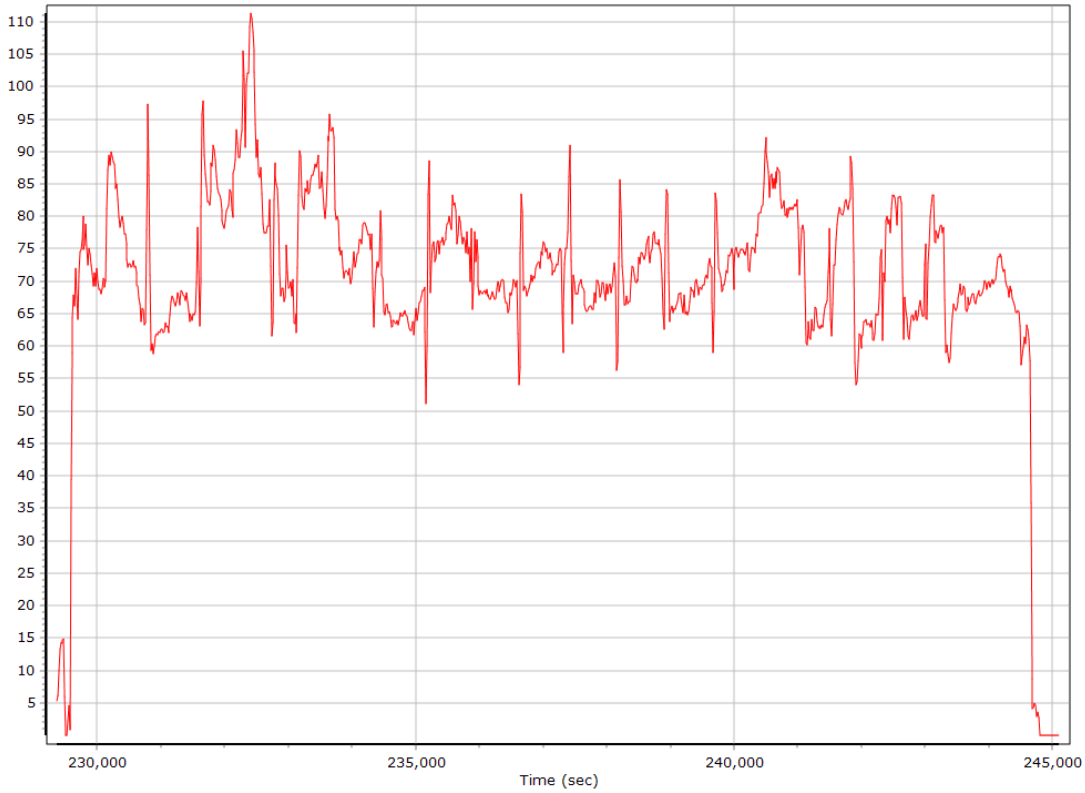
North/East Velocity



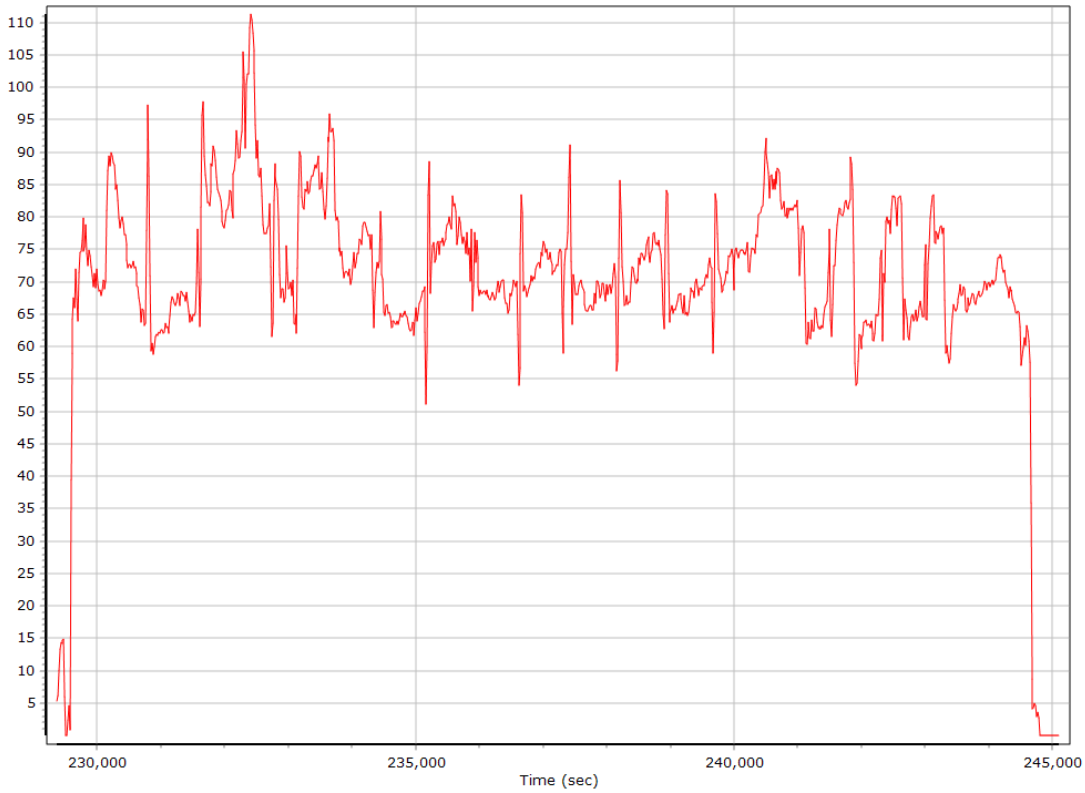
Down Velocity



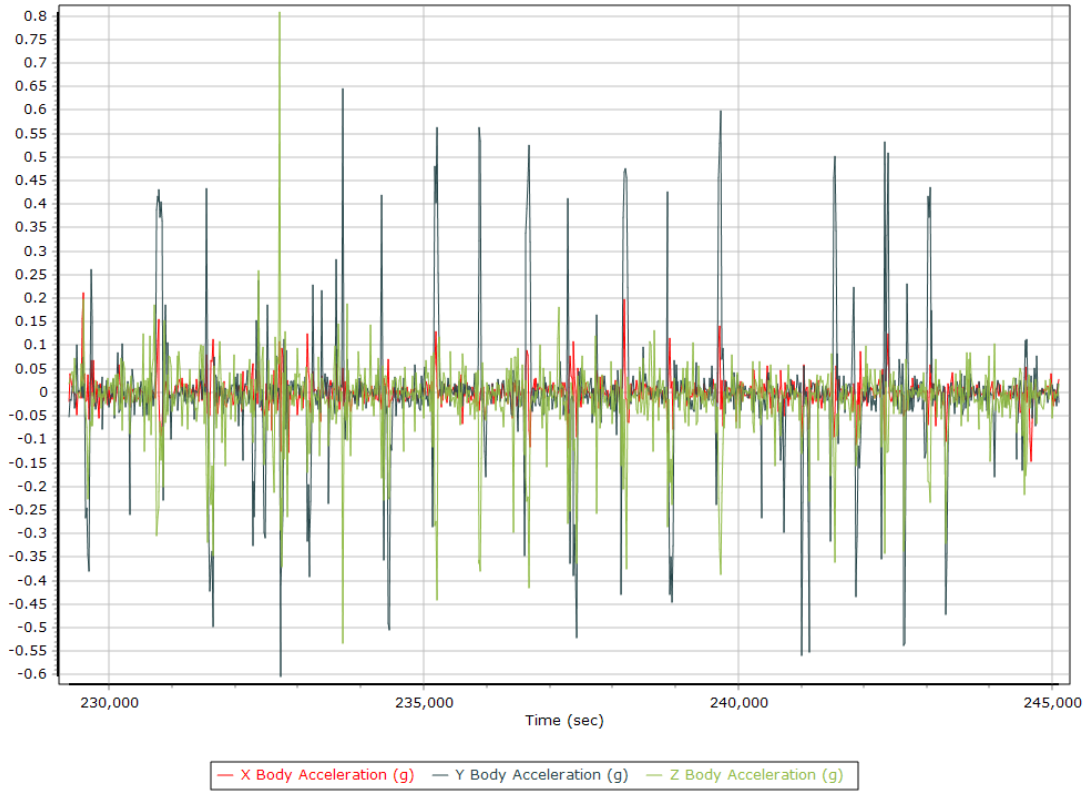
Total Speed



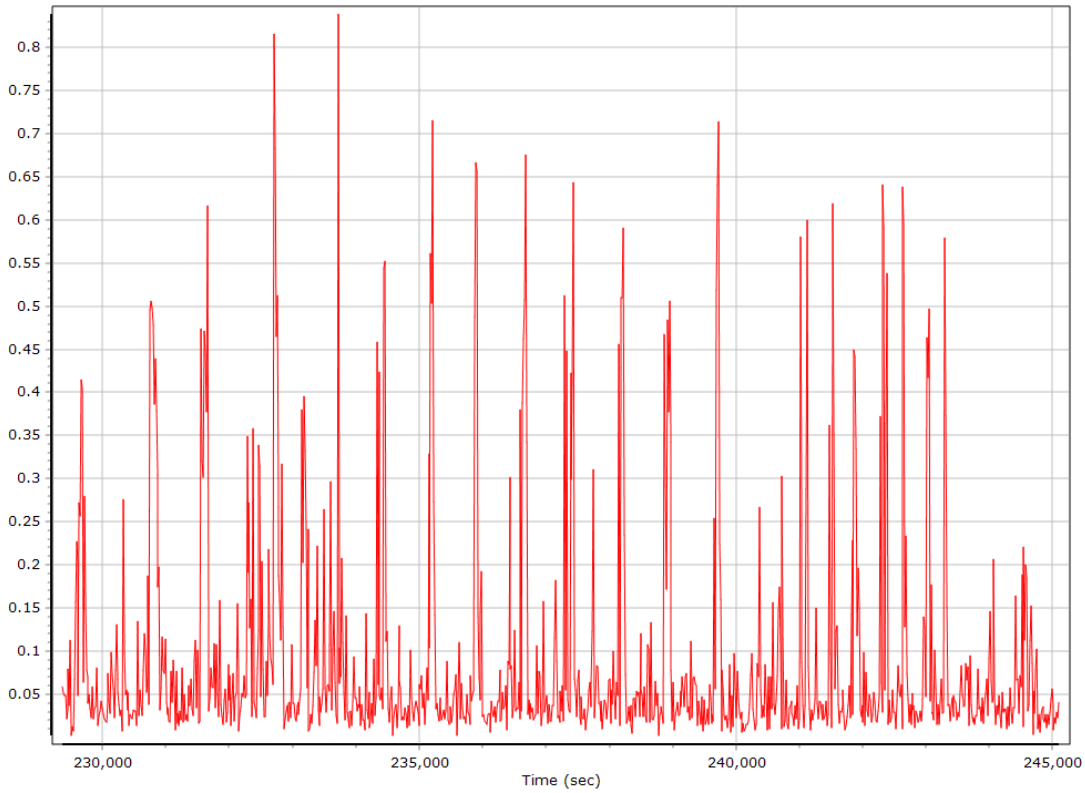
Ground Speed



Body Acceleration



Total Body Acceleration



Body Angular Rate

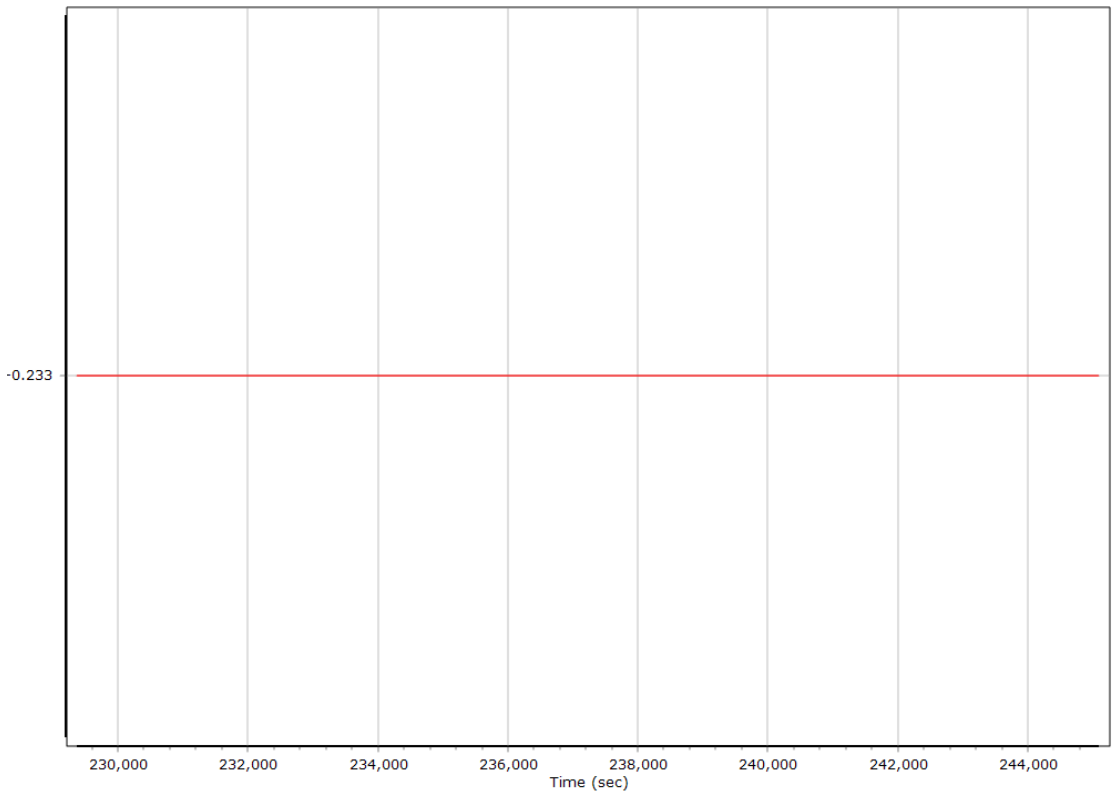
GNSS-Inertial Processor Configuration

Processing mode	IN-Fusion Trimble RTX Nav		
Stabilized mount	True		
Processing start time	228909.000 (11/19/2019 15:34:51)		
Processing end time	245108.000 (11/19/2019 20:04:50)		
Initial attitude source	Real-Time VNAV/RNAV Attitude		
IMU Sensor Context	Processing with Onboard IMU		
Gimbal to IMU lever arm [m]	0.000	0.000	0.000
Gimbal to IMU mounting angles [deg]	0.000	0.000	0.000
Gimbal to Primary GNSS lever arm [m]	-0.233	-0.013	-0.930
Gimbal to Primary GNSS lever arm std dev [m]	0.030	0.030	0.030
Aircraft to Reference mounting angles [deg]	0.000	0.000	0.000

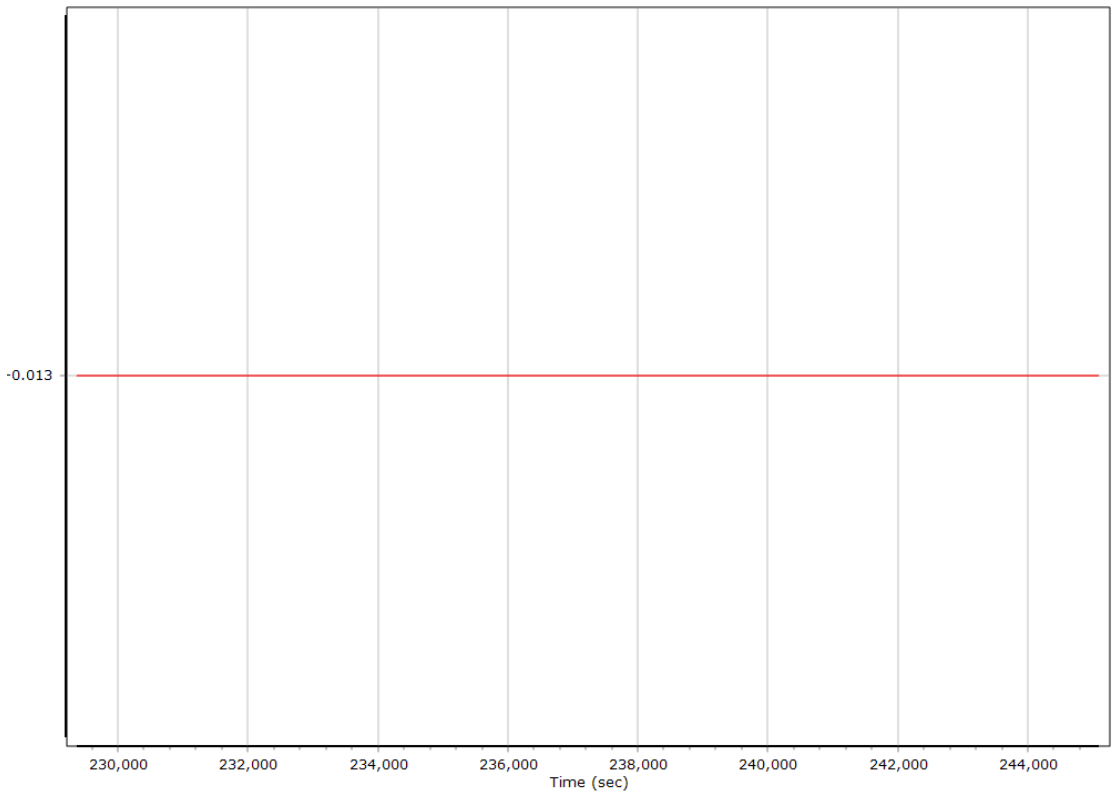
Calibrated Installation Parameters

Reference-Primary GNSS Lever Arm

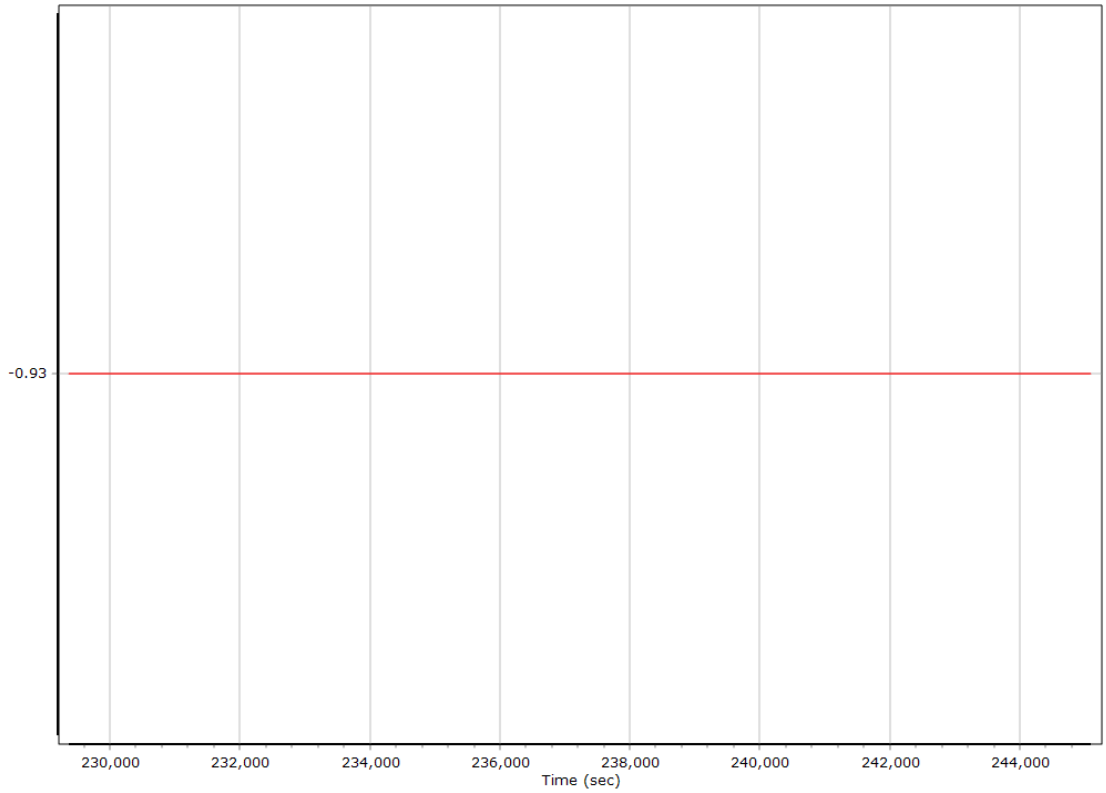
X Reference-Primary GNSS Lever Arm (m)



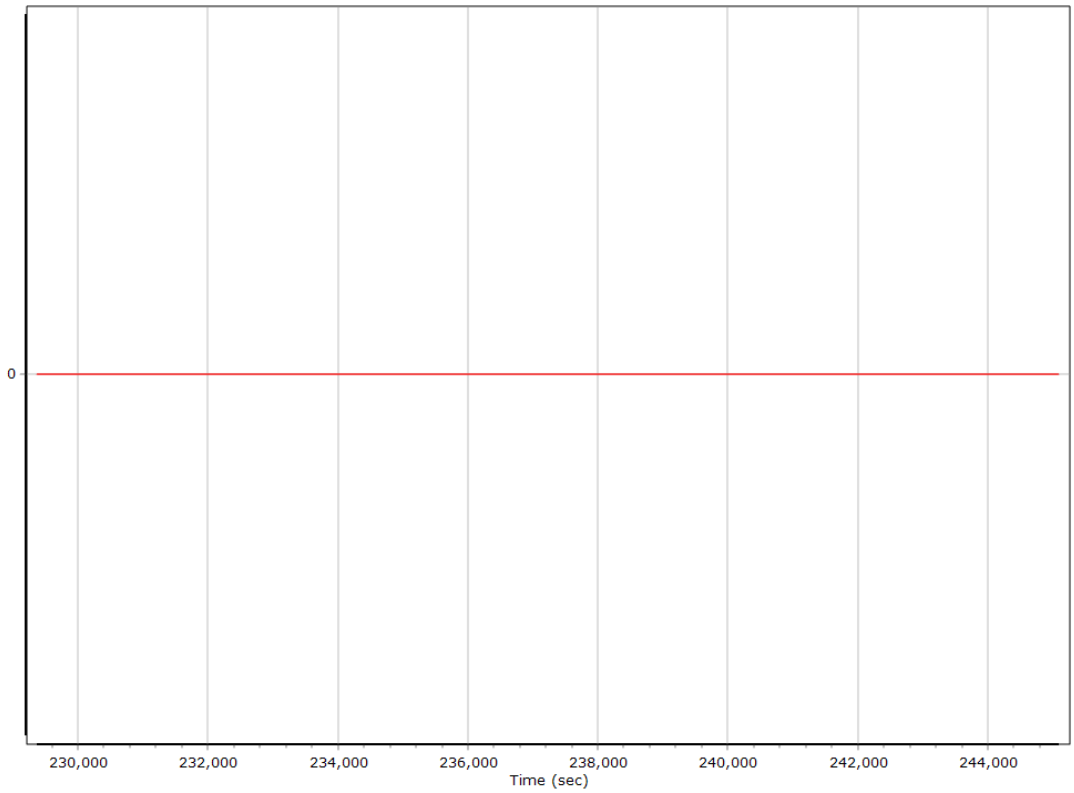
Y Reference-Primary GNSS Lever Arm (m)



Z Reference-Primary GNSS Lever Arm (m)



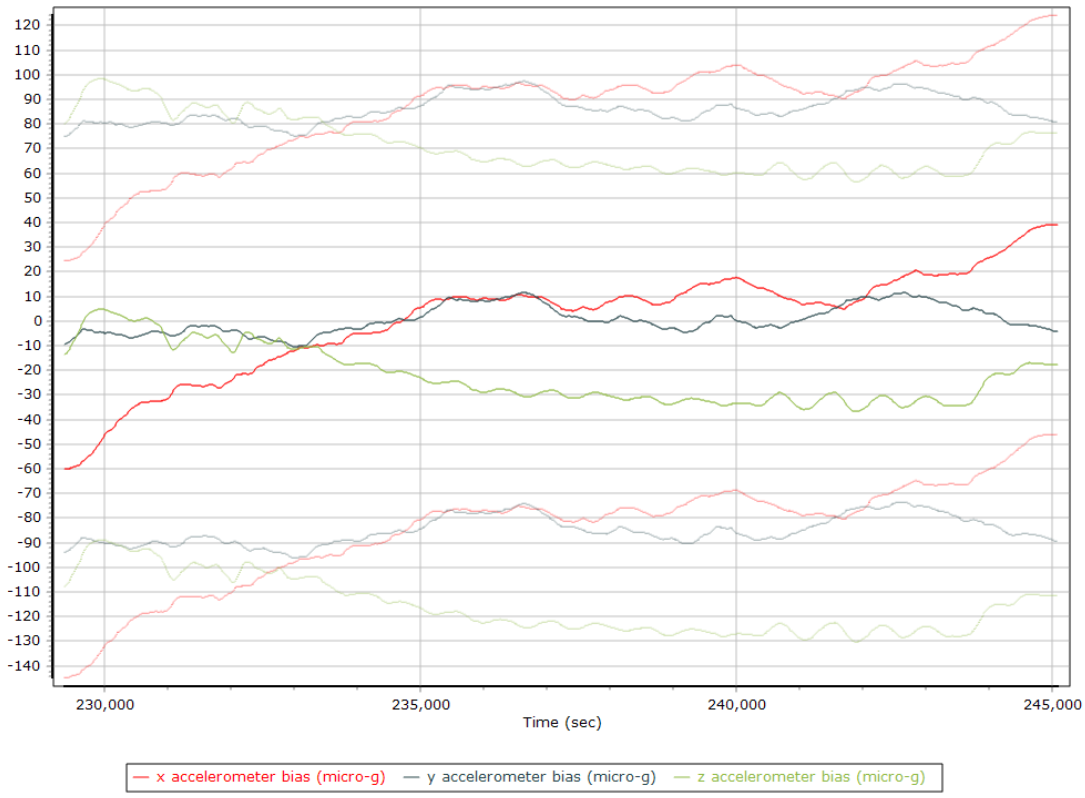
Reference-Primary GNSS Lever Arm Figure of Merit



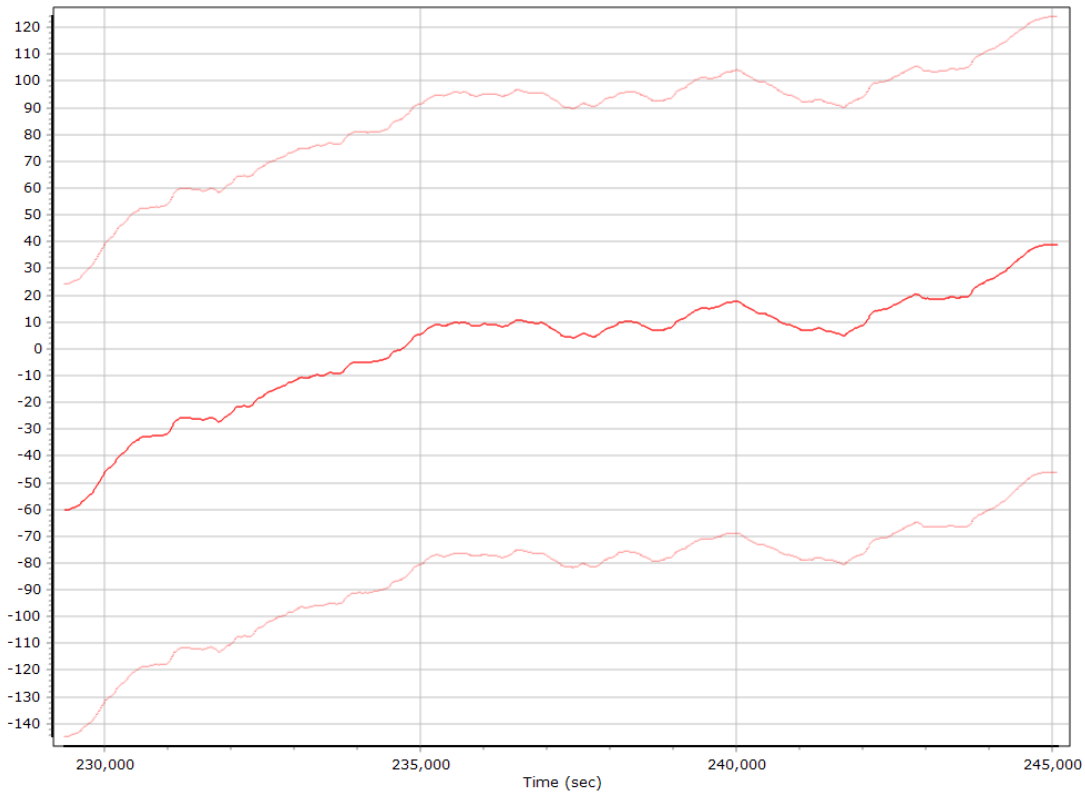
Smoothed IN-Fusion QC

Smoothed Estimated Errors, Reference Frame

Accelerometer Bias (micro-g)



X Accelerometer Bias (micro-g)



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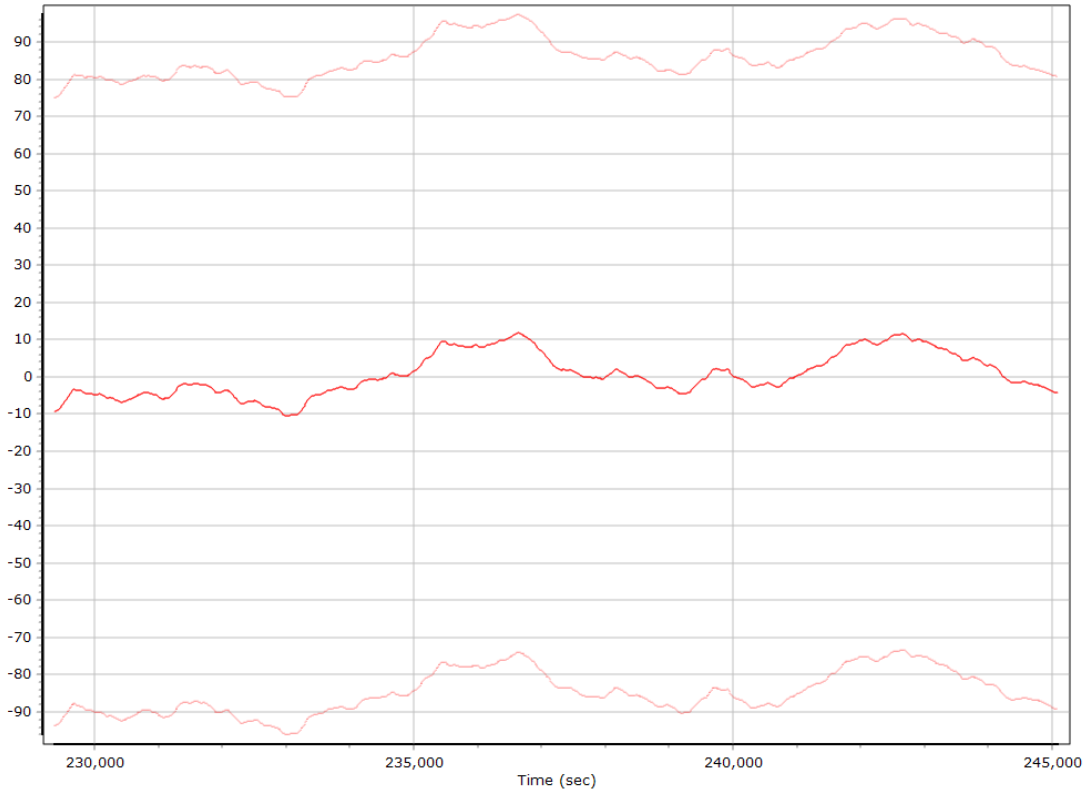
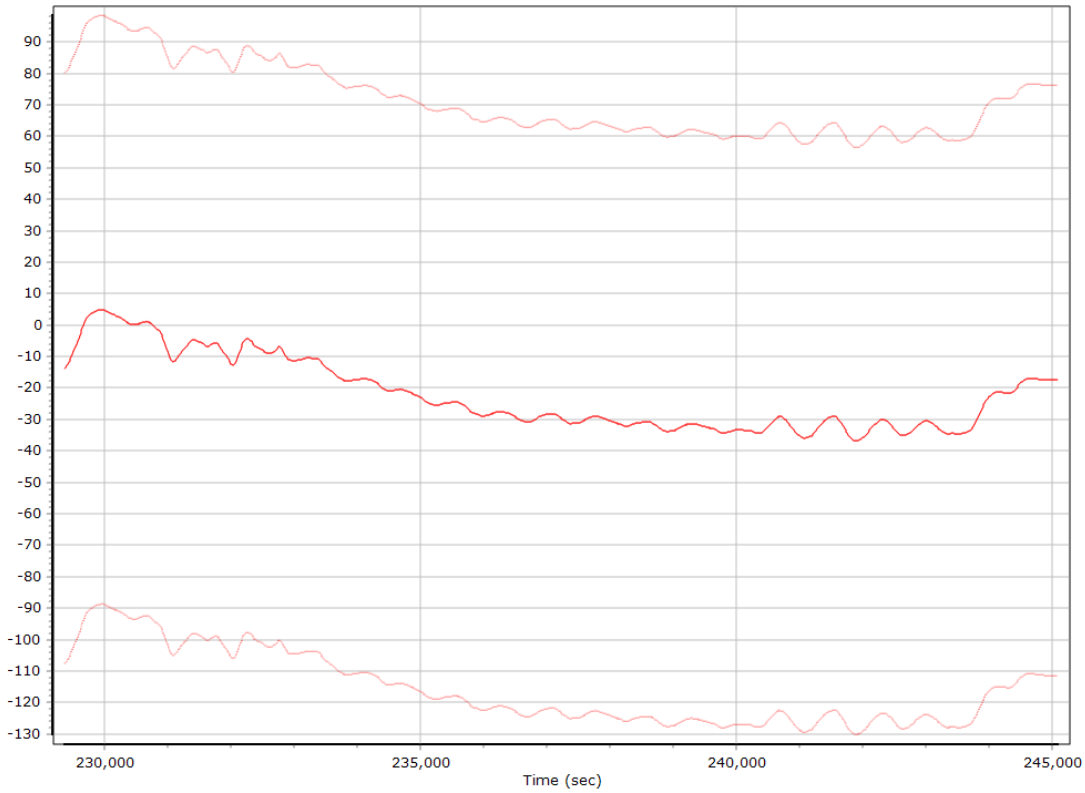
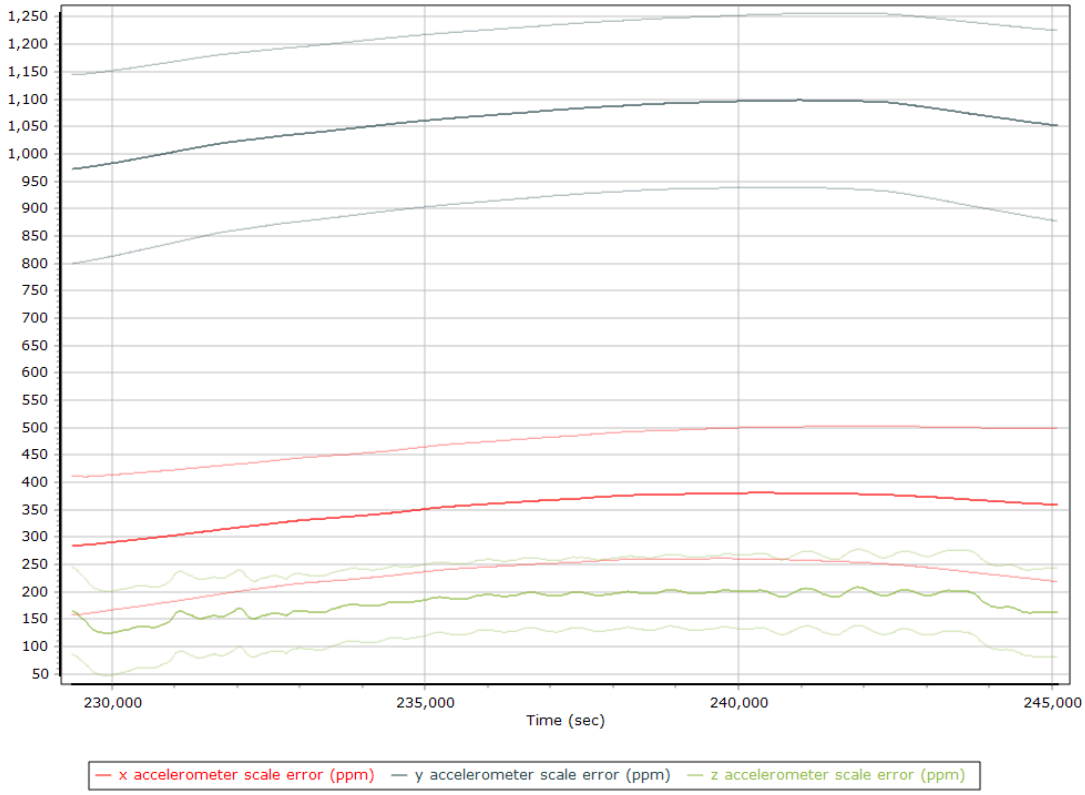


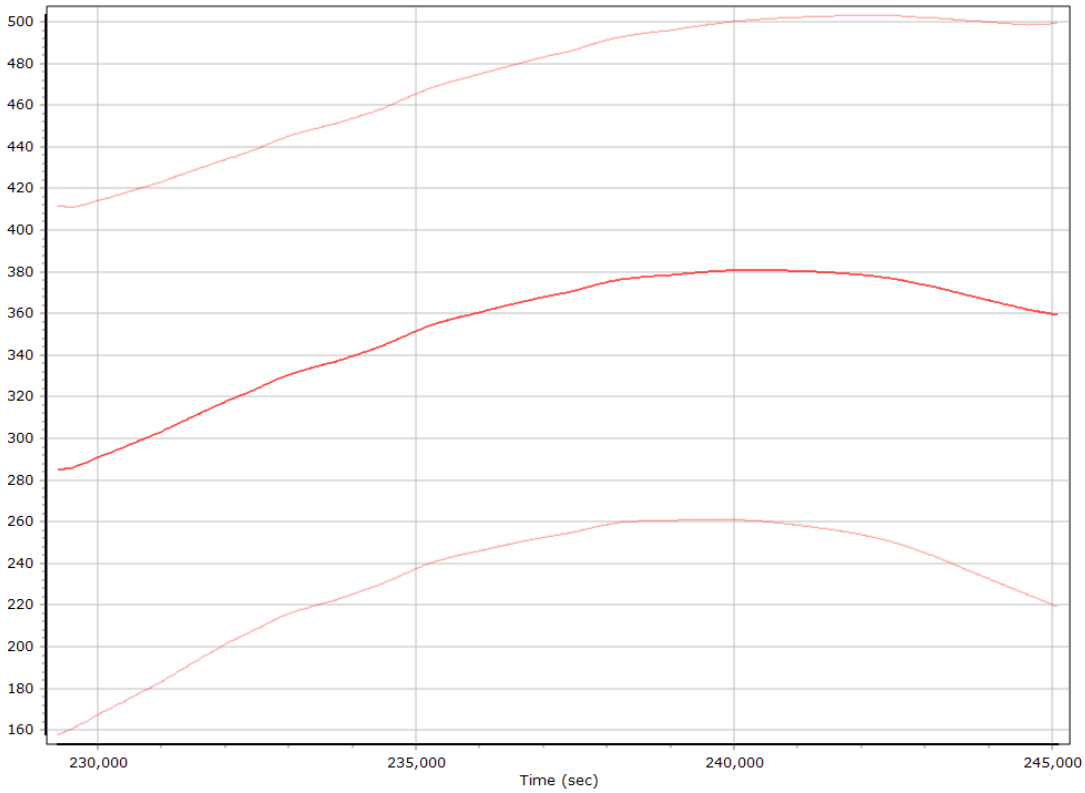
Z Accelerometer Bias (micro-g)



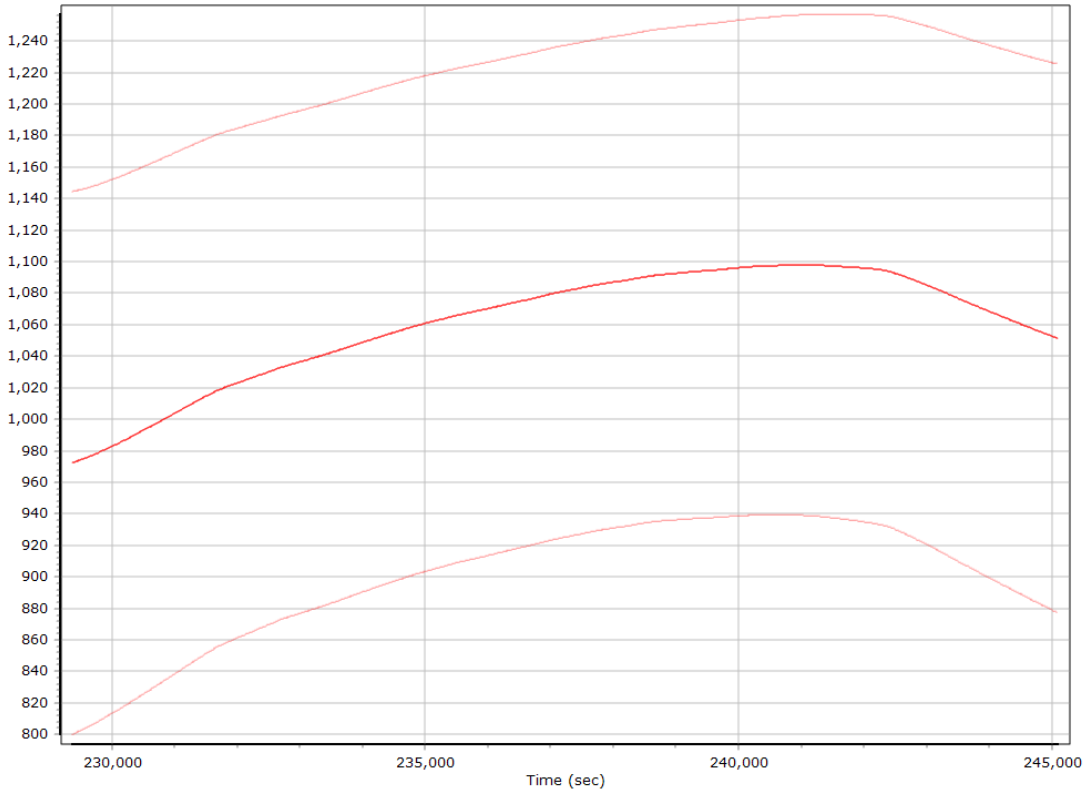
Accelerometer Scale Error (ppm)



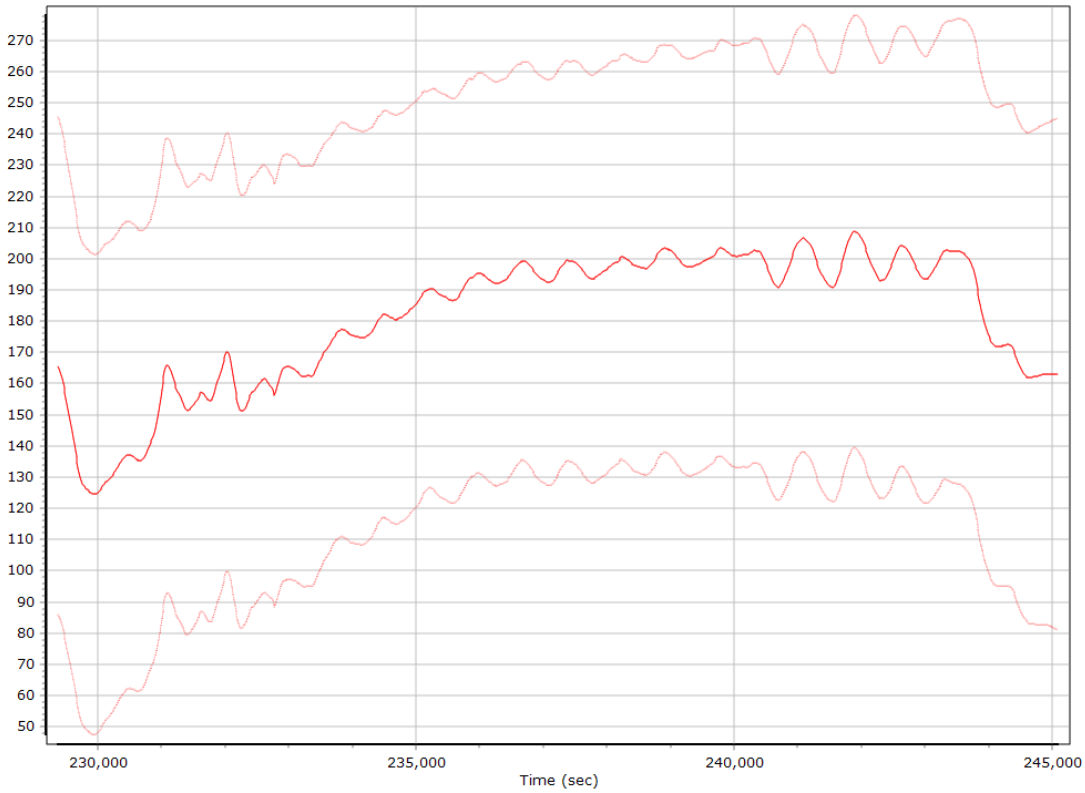
X Accelerometer Scale Error (ppm)



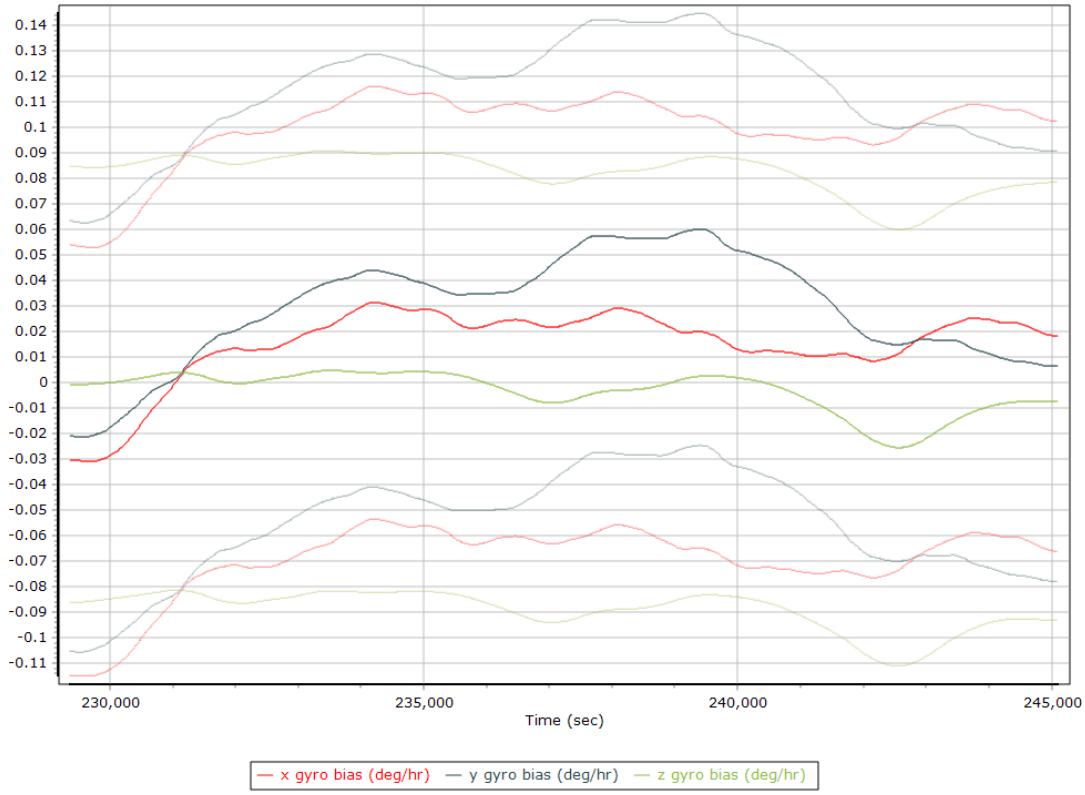
Y Accelerometer Scale Error (ppm)



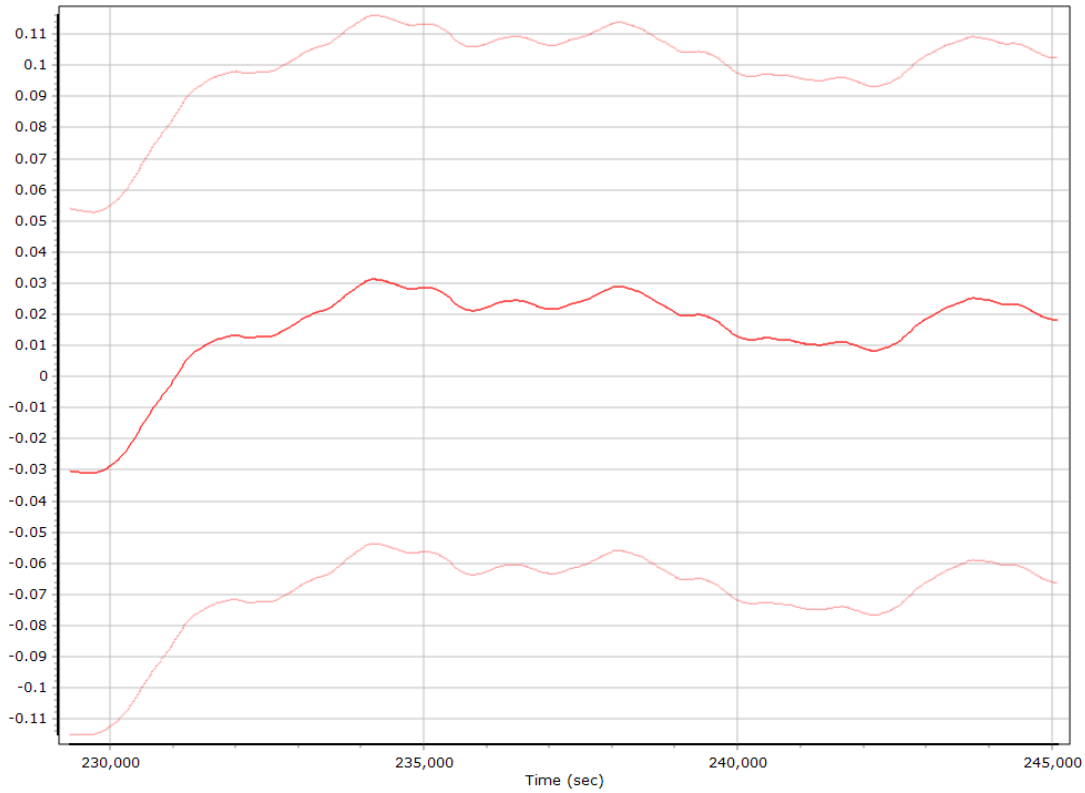
Z Accelerometer Scale Error (ppm)



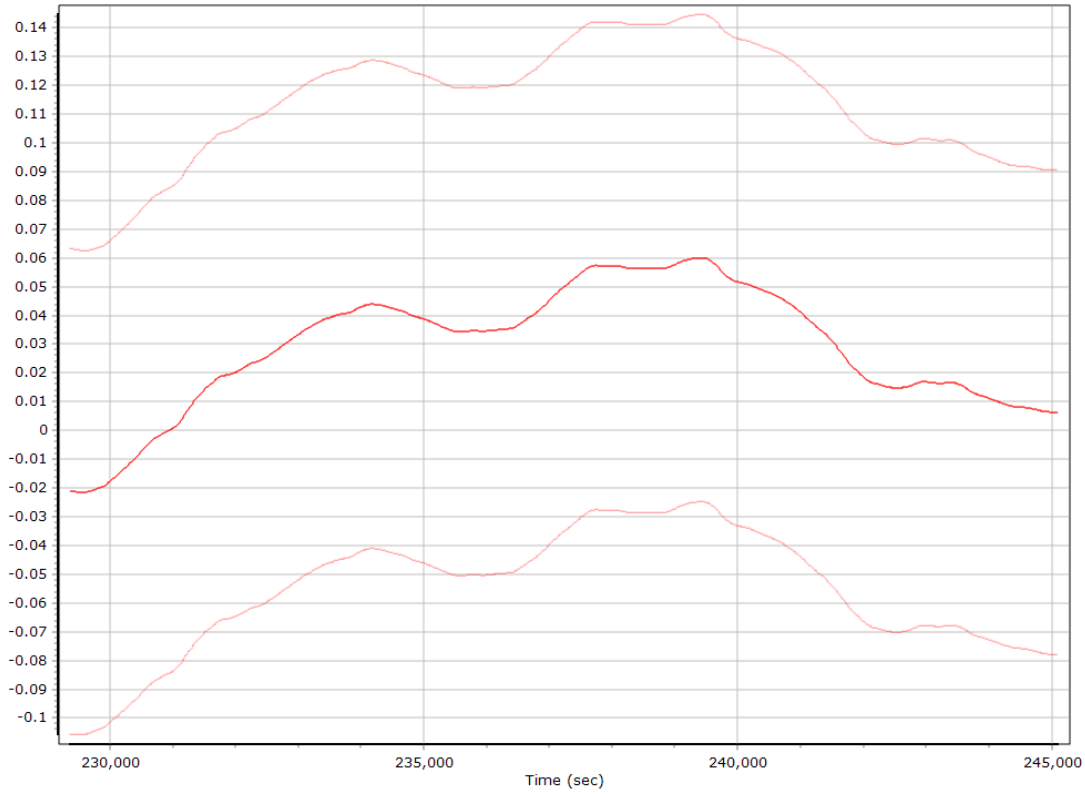
Gyro Bias (deg/h)



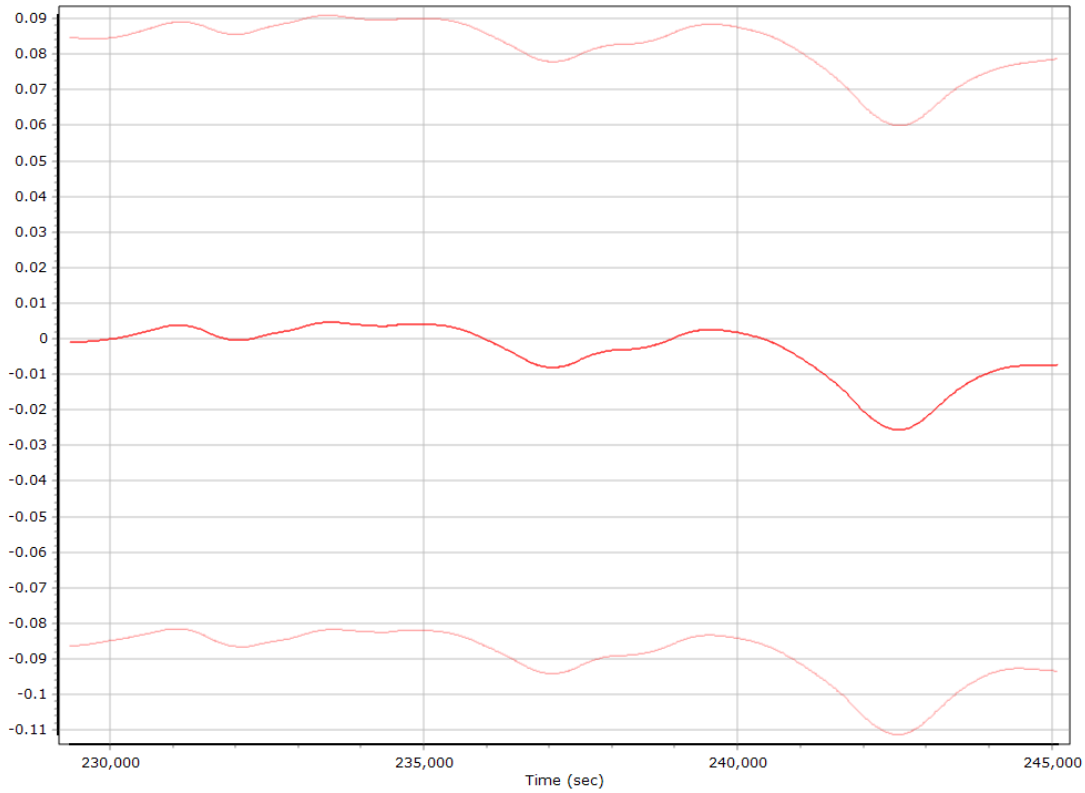
X Gyro Bias (deg/h)



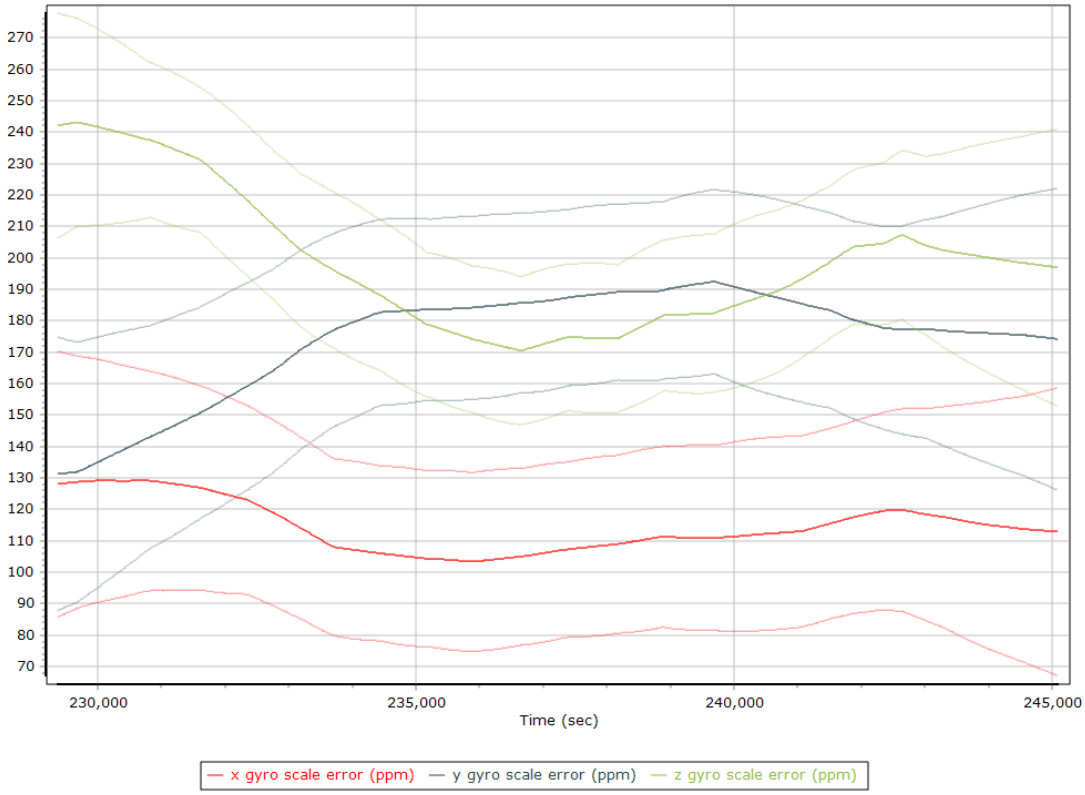
Y Gyro Bias (deg/h)



Z Gyro Bias (deg/h)



Gyro Scale Error (ppm)



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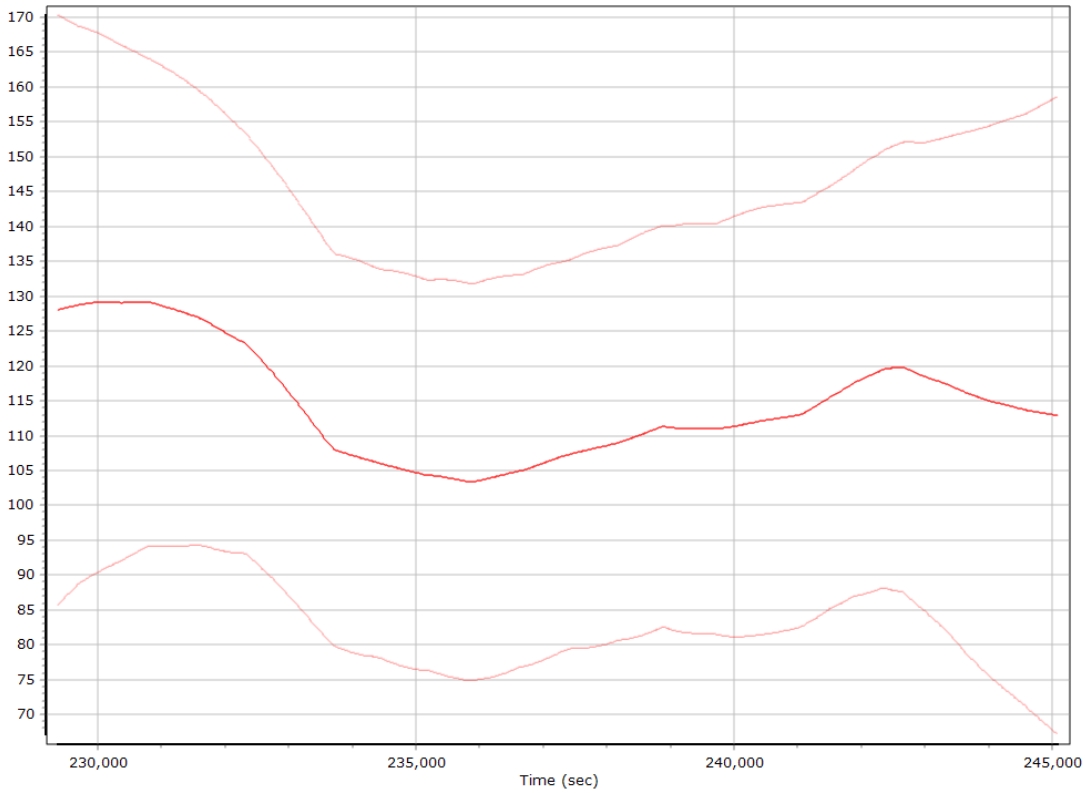
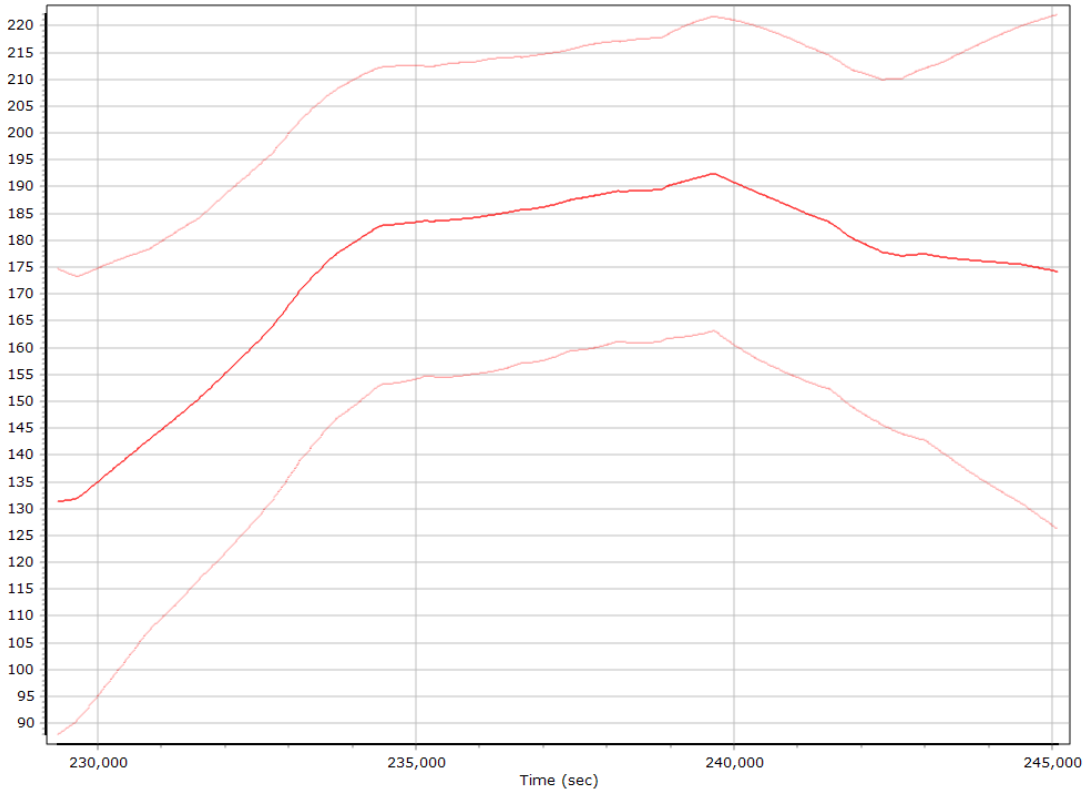
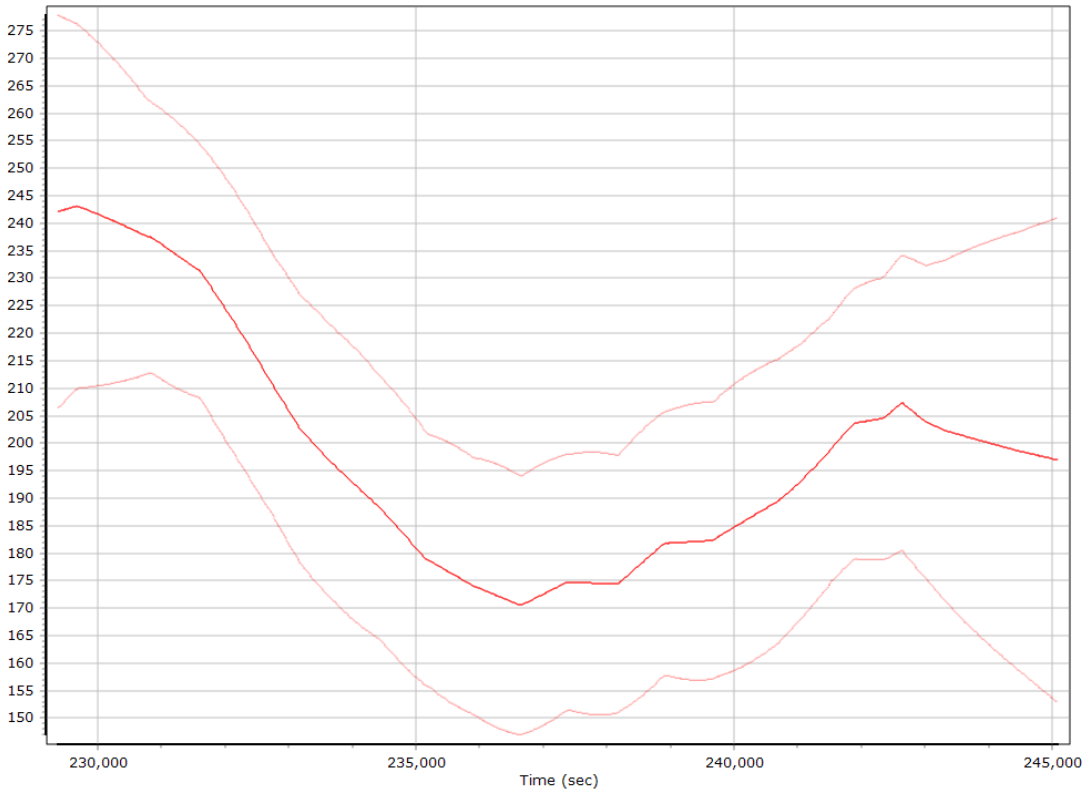


Y Gyro Scale Error (ppm)

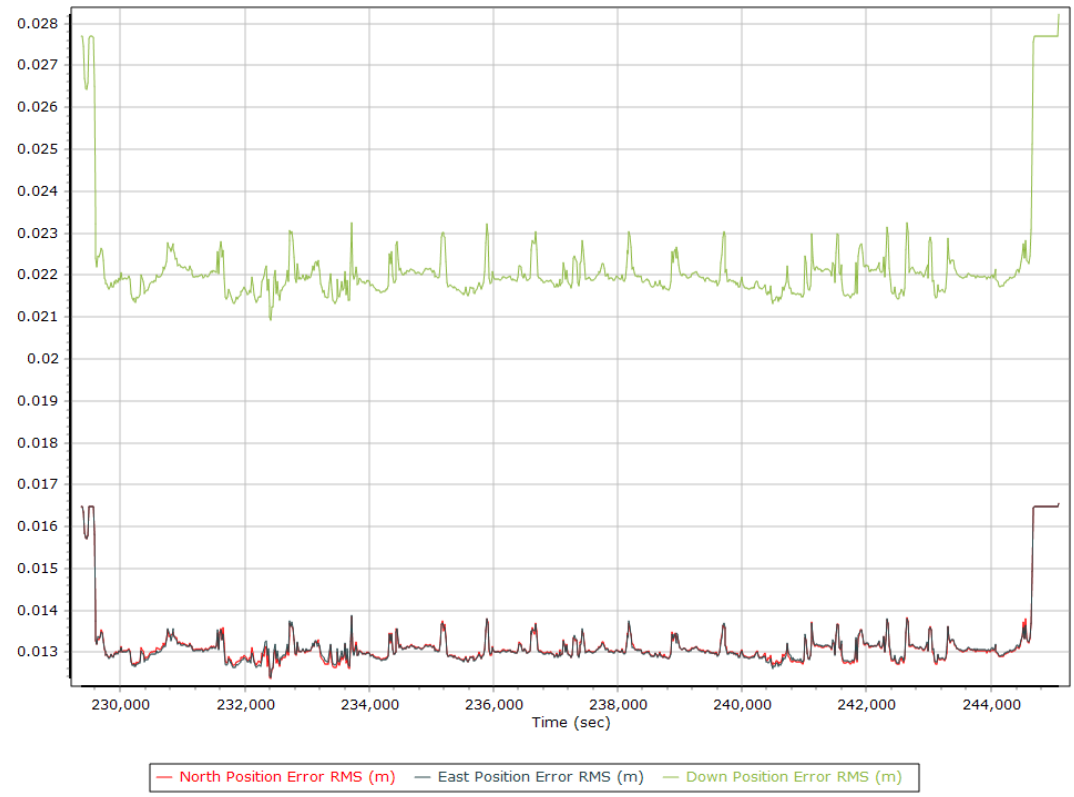


Z Gyro Scale Error (ppm)

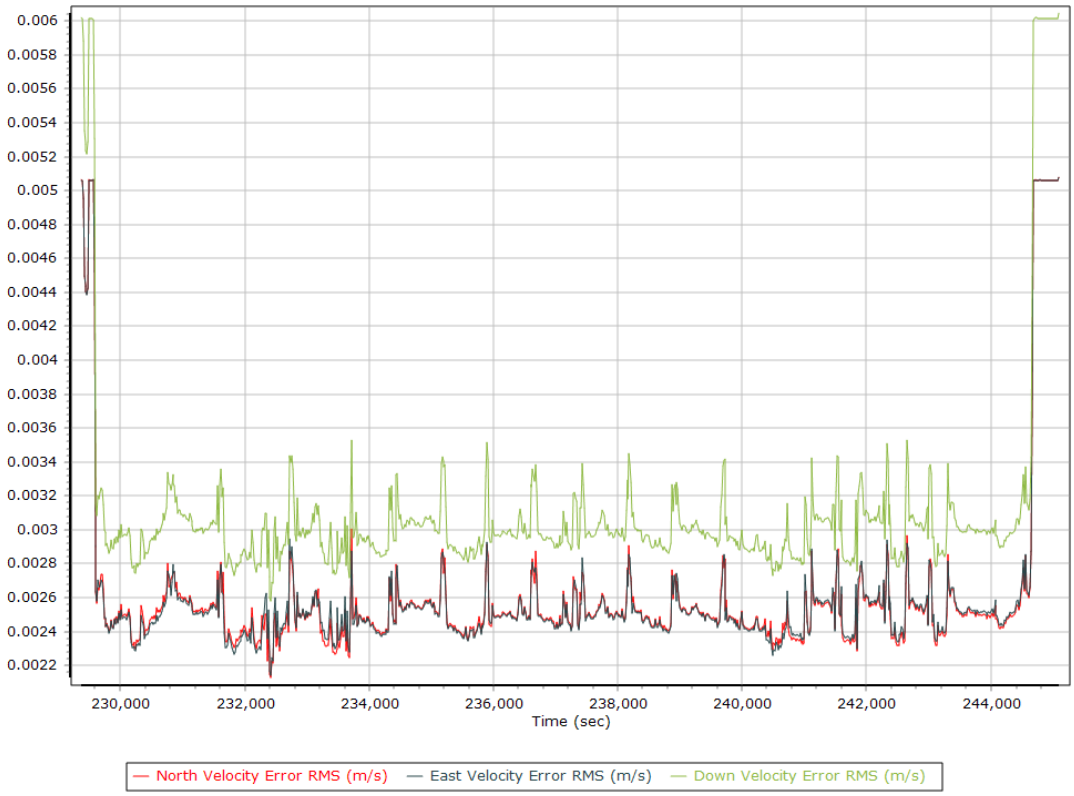


Smoothed Performance Metrics

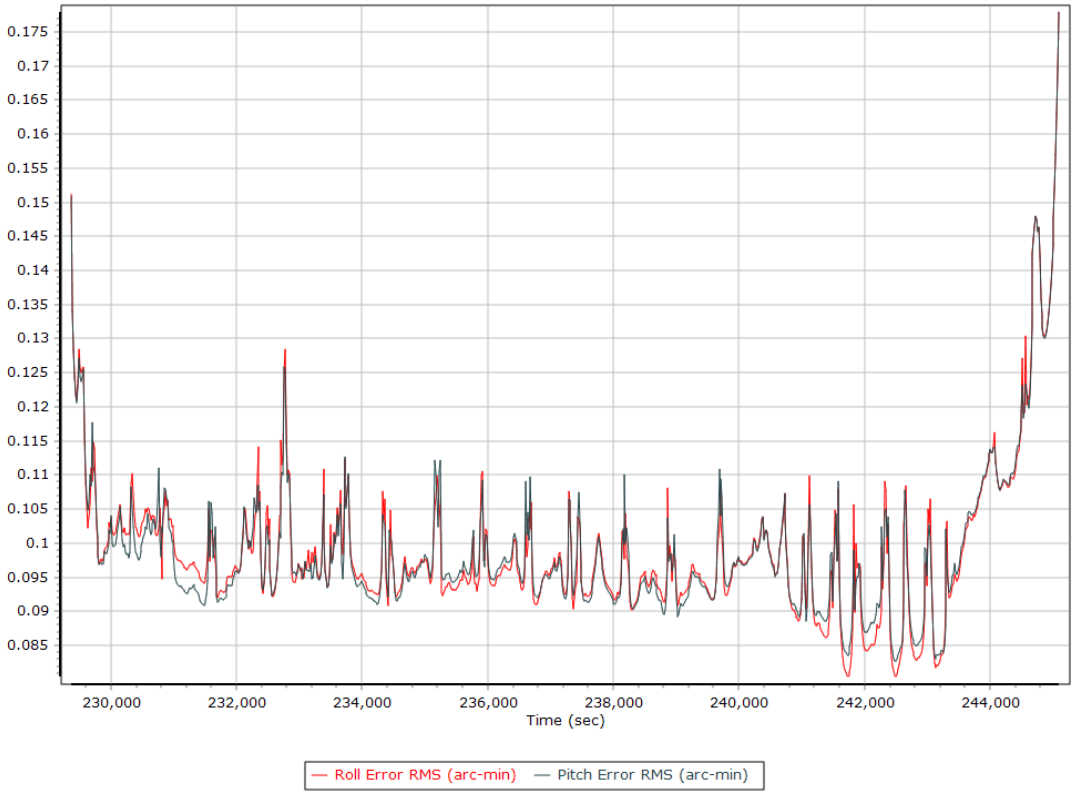
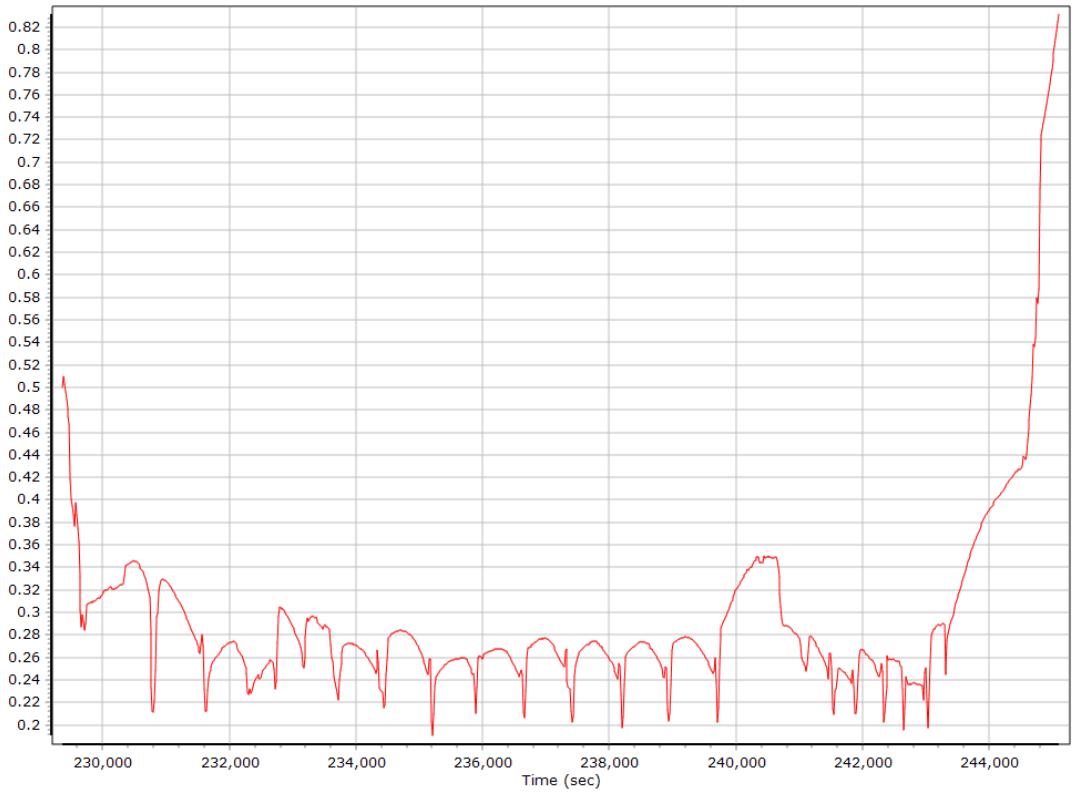
Position Error RMS (m)



Velocity Error RMS (m/s)



Roll/Pitch Error RMS (arc-min)



Heading Error RMS (arc-min)