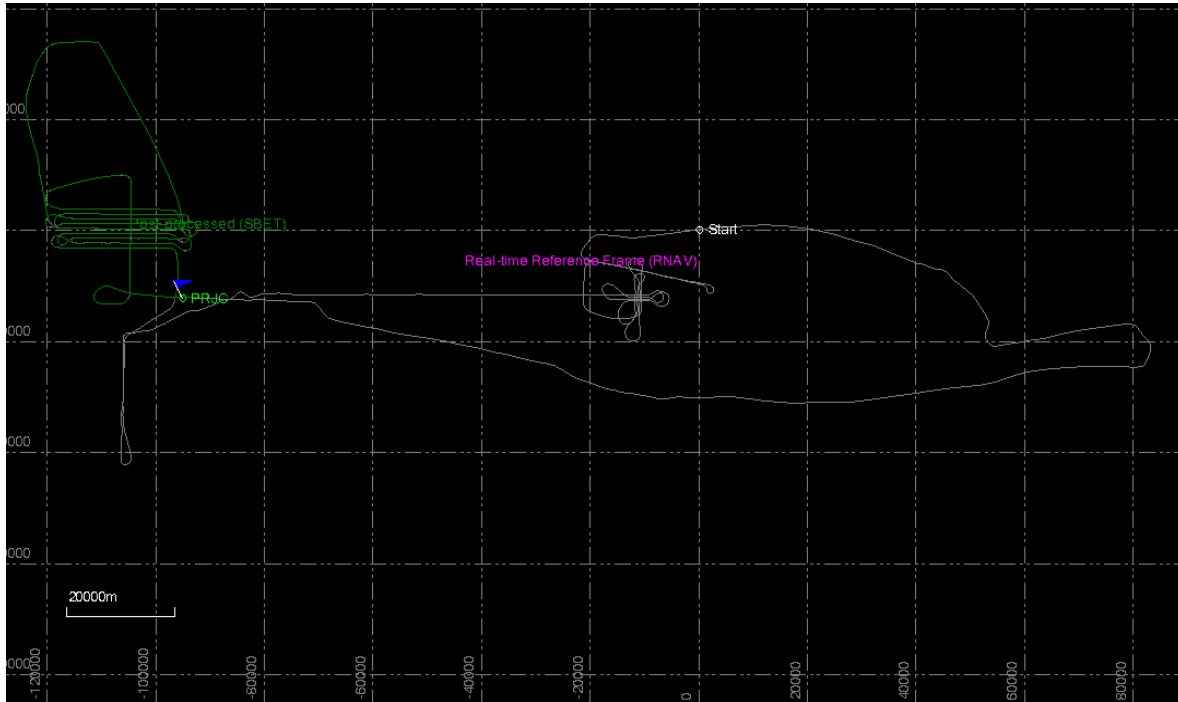


AZT18122A

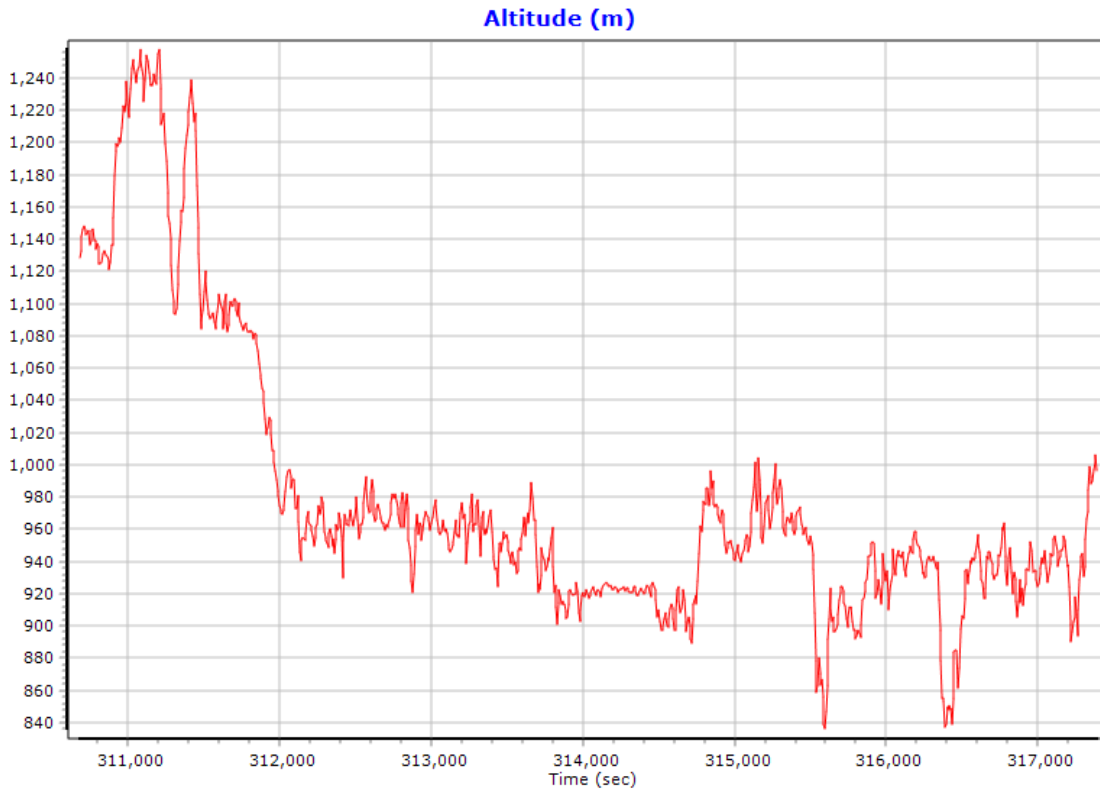


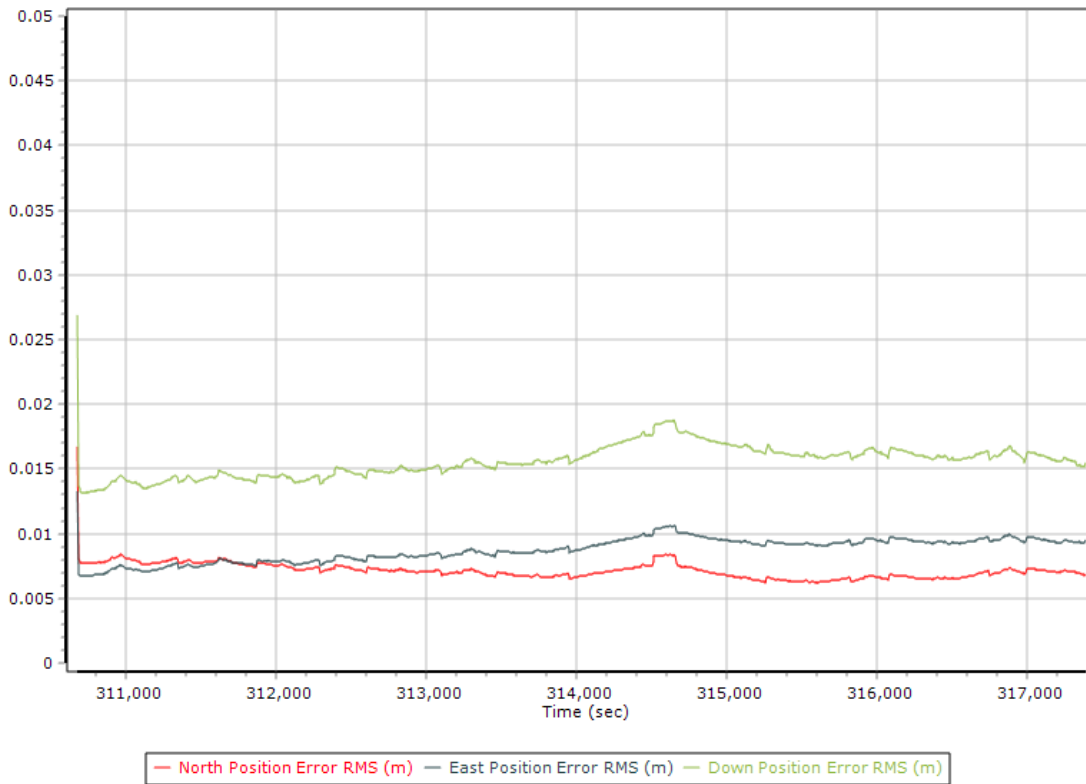
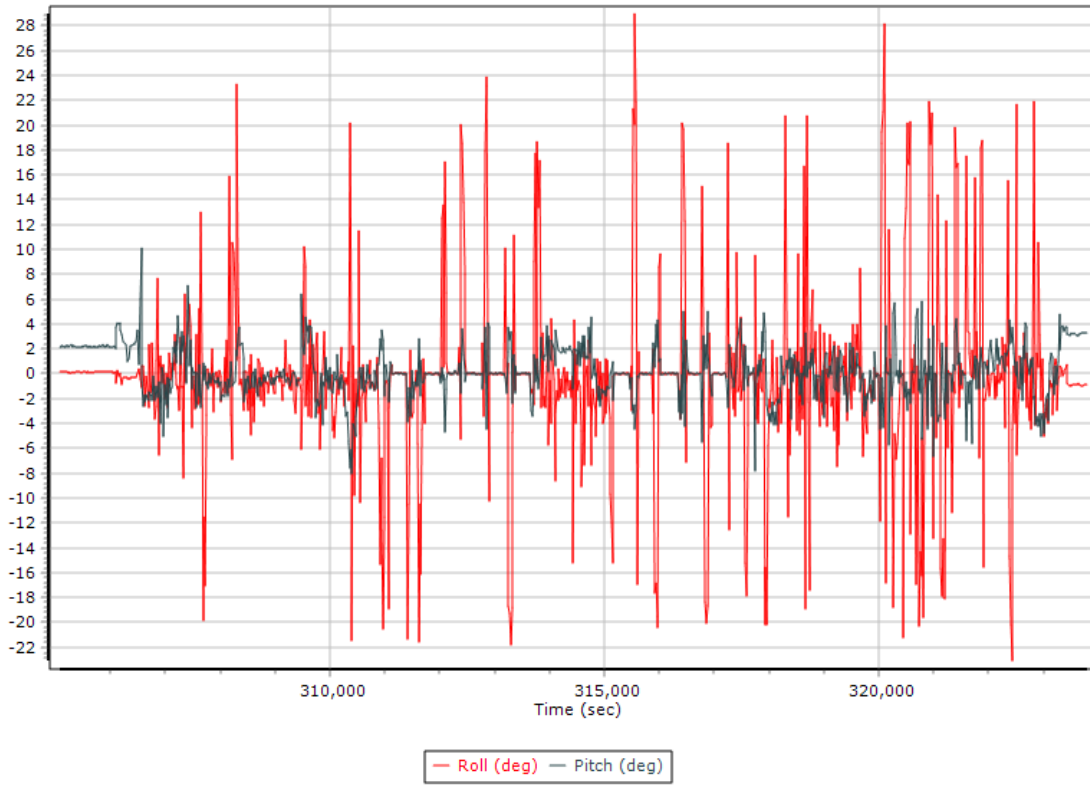
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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		

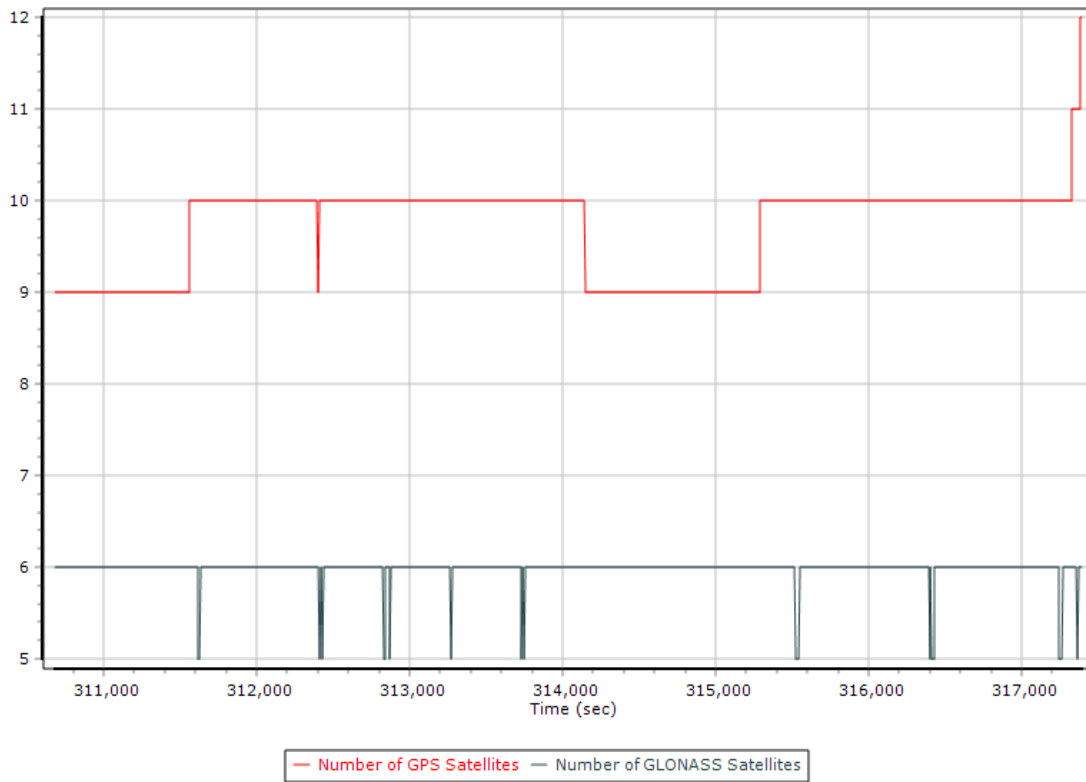
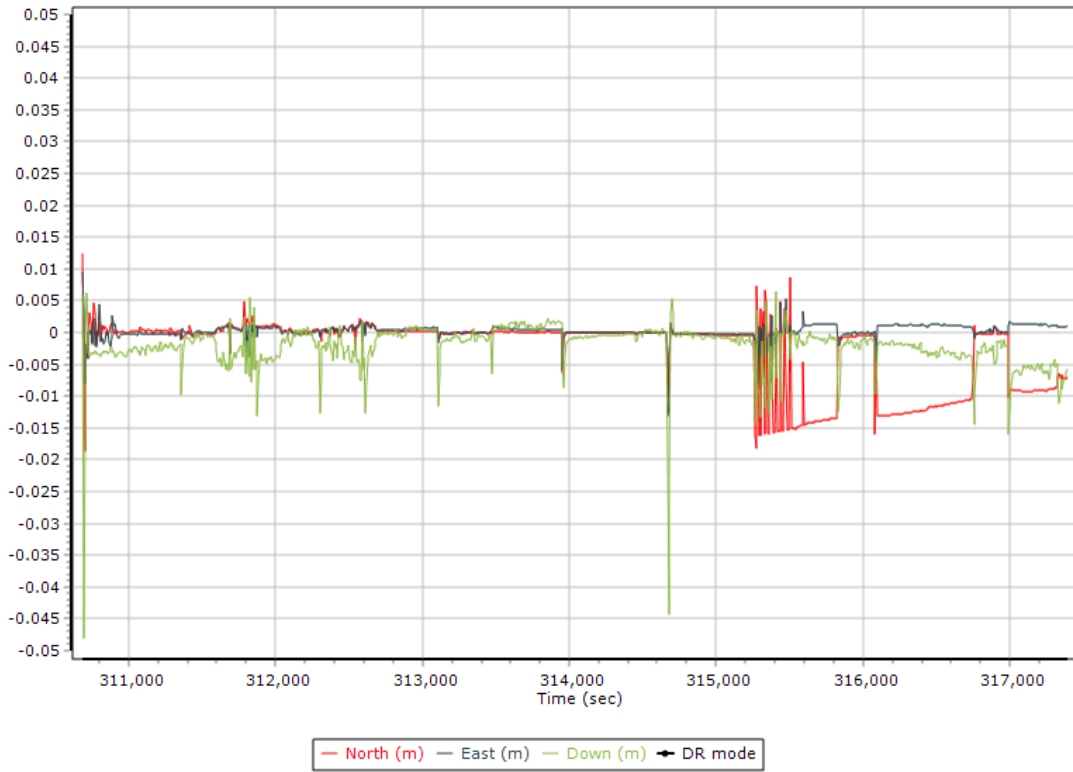
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

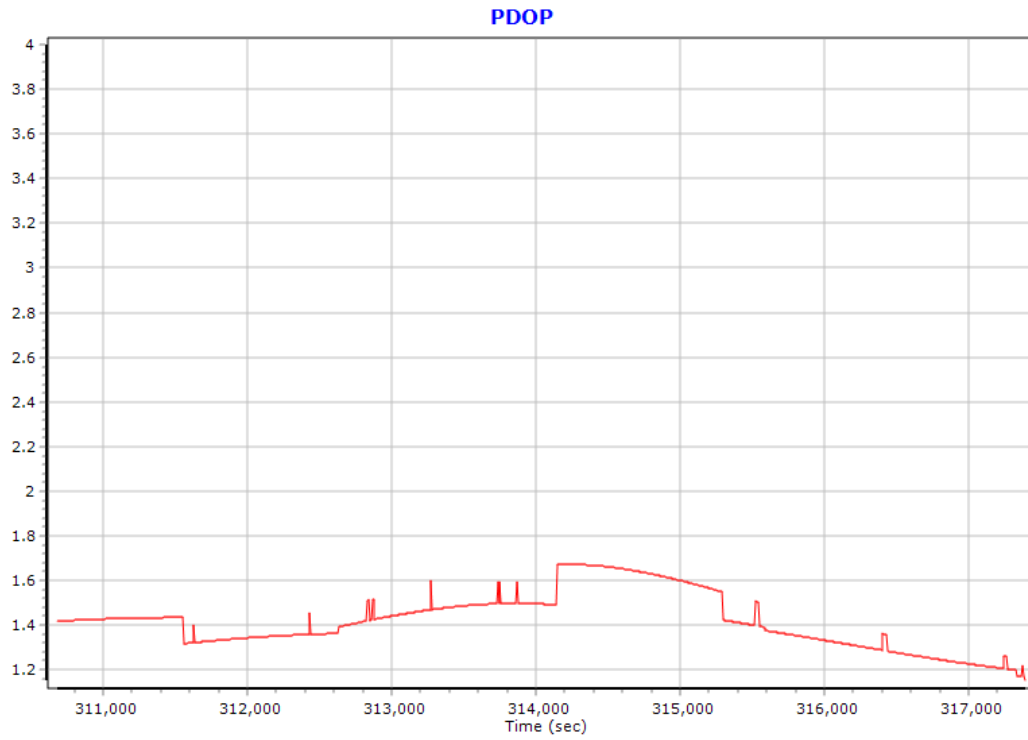
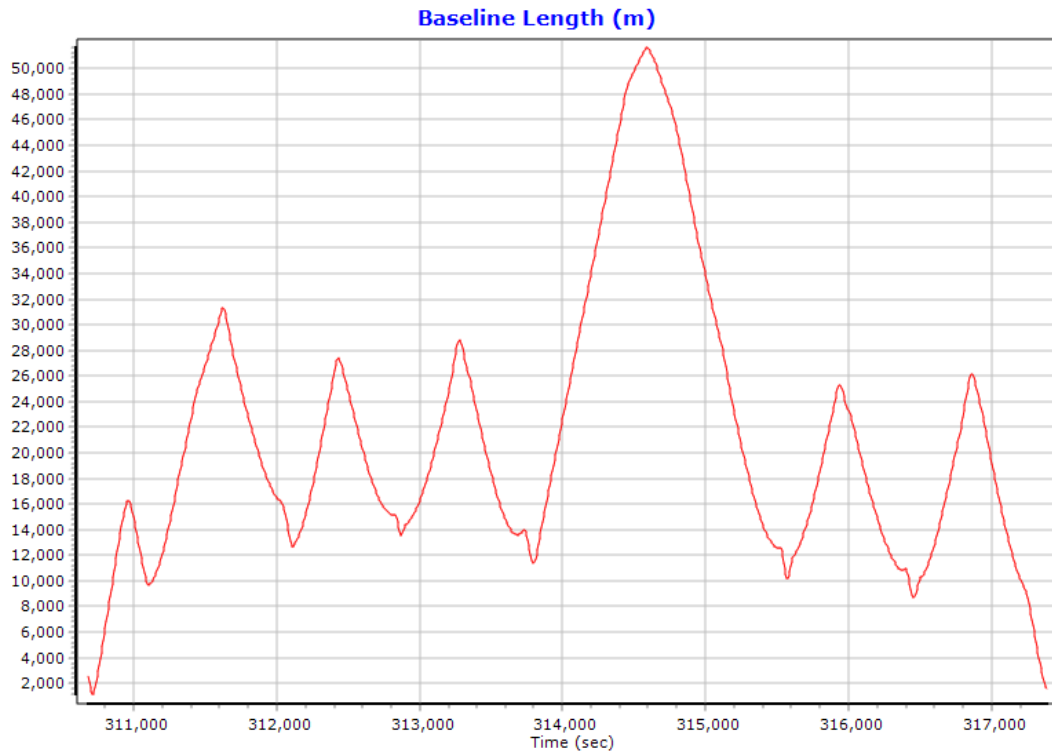
Timing

Start	310678.337	Data	Incr. (sec)
End	317399.906	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		

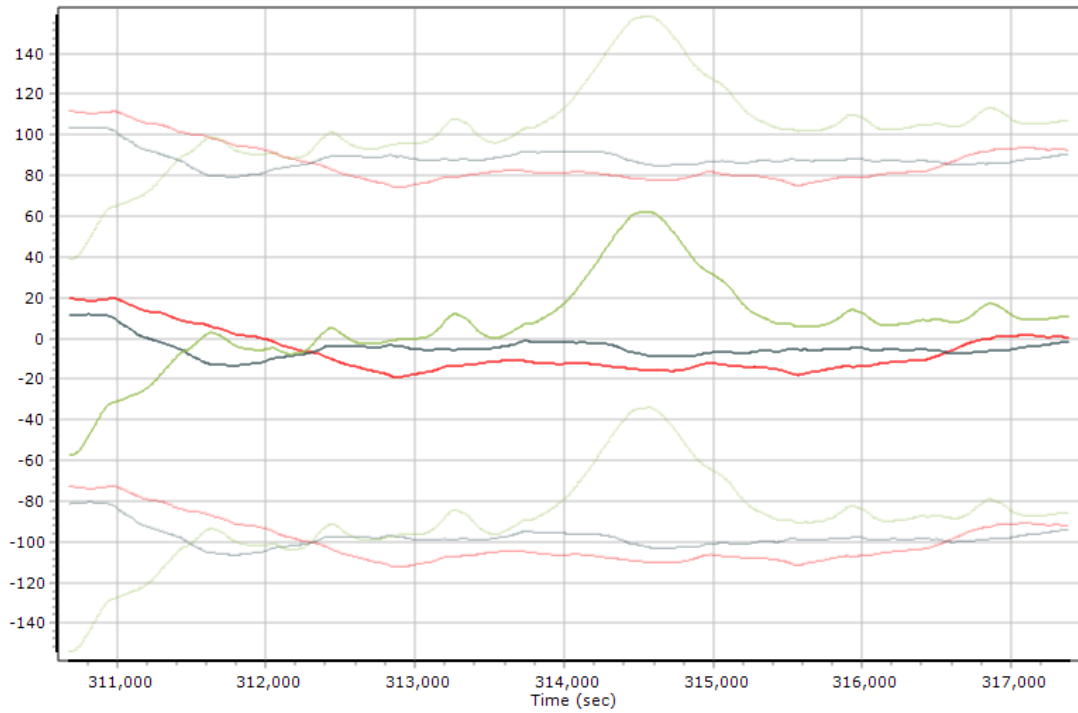




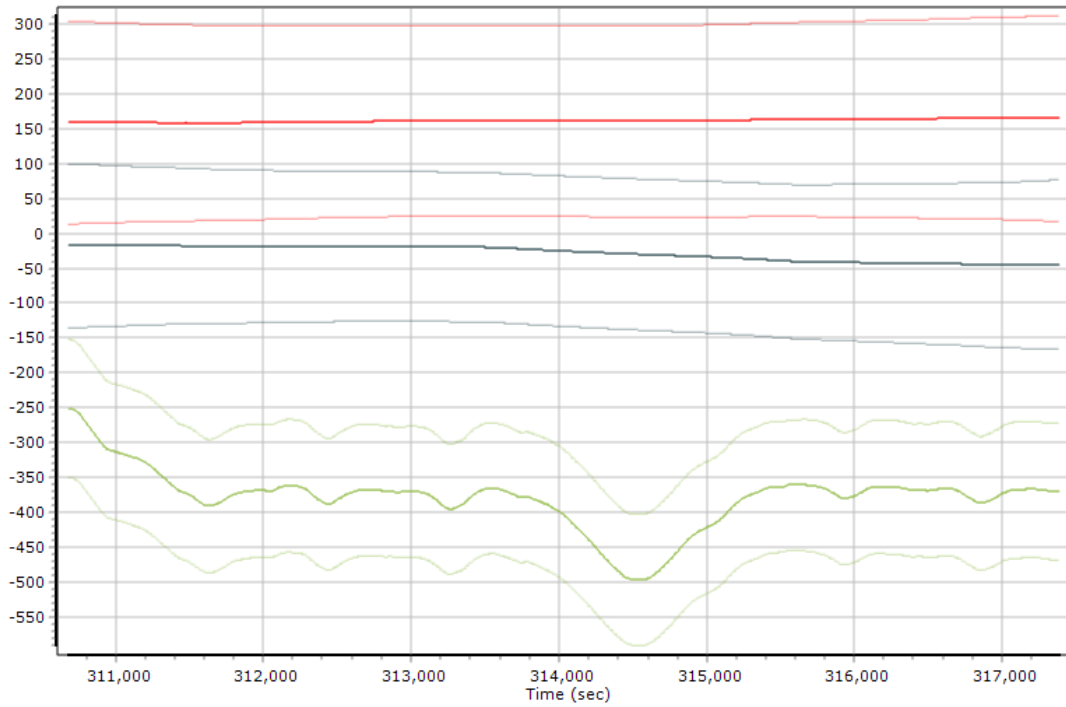




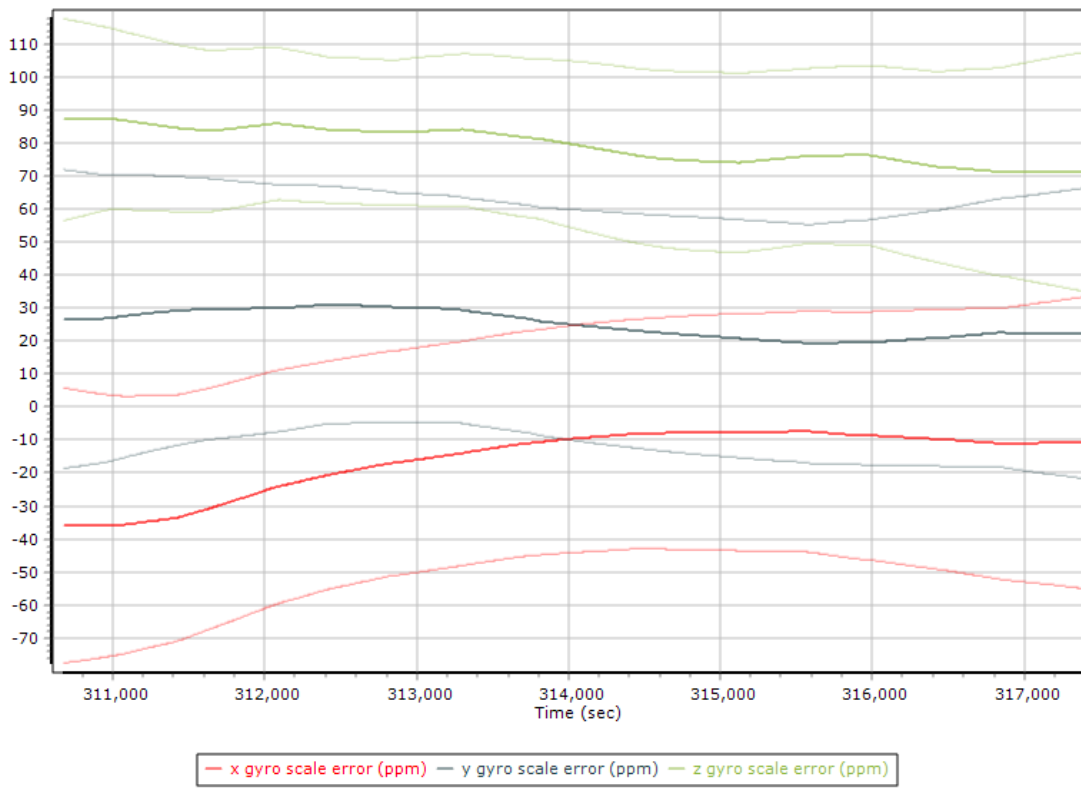
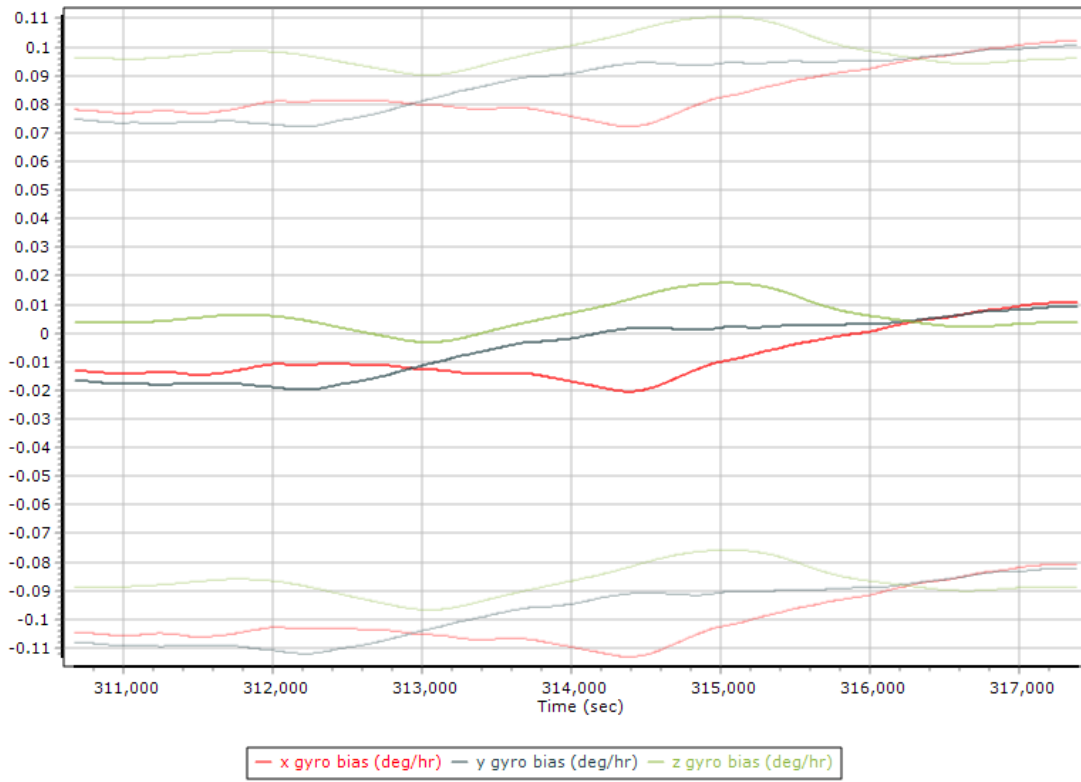
Sensor Errors



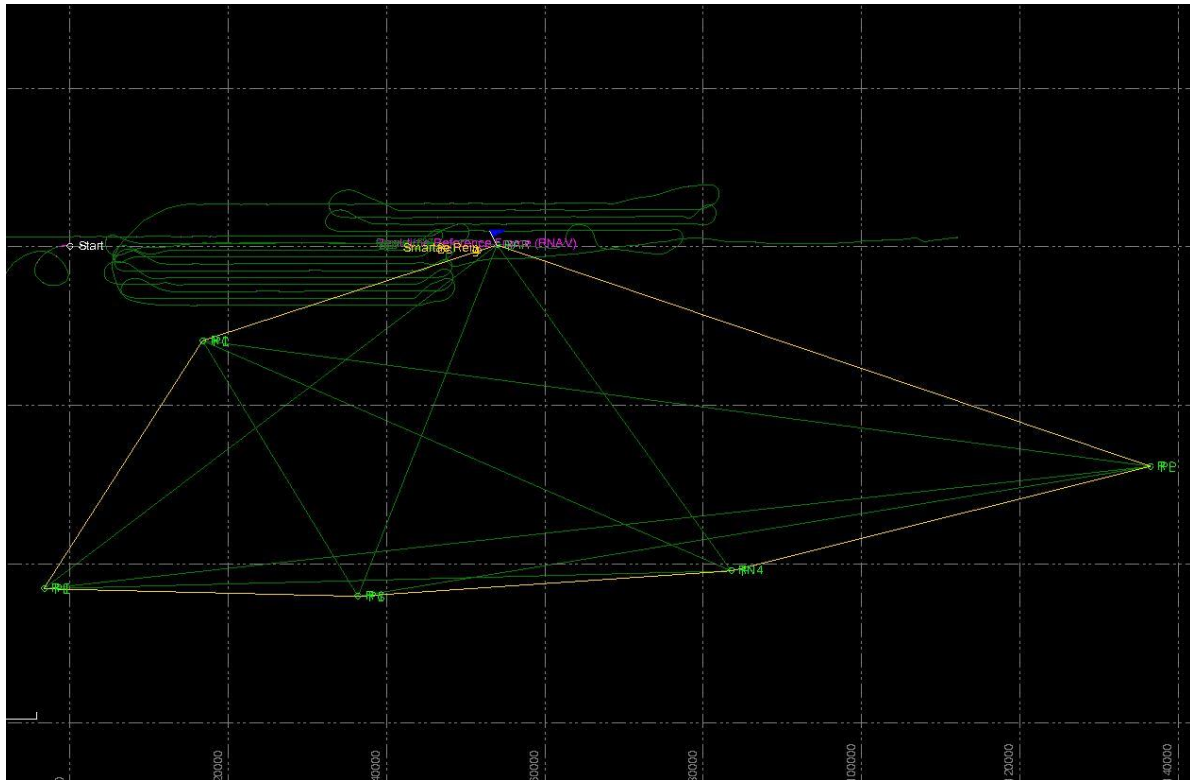
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



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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.			

Timing

Start: 5/5/2018 11:22:27 PM

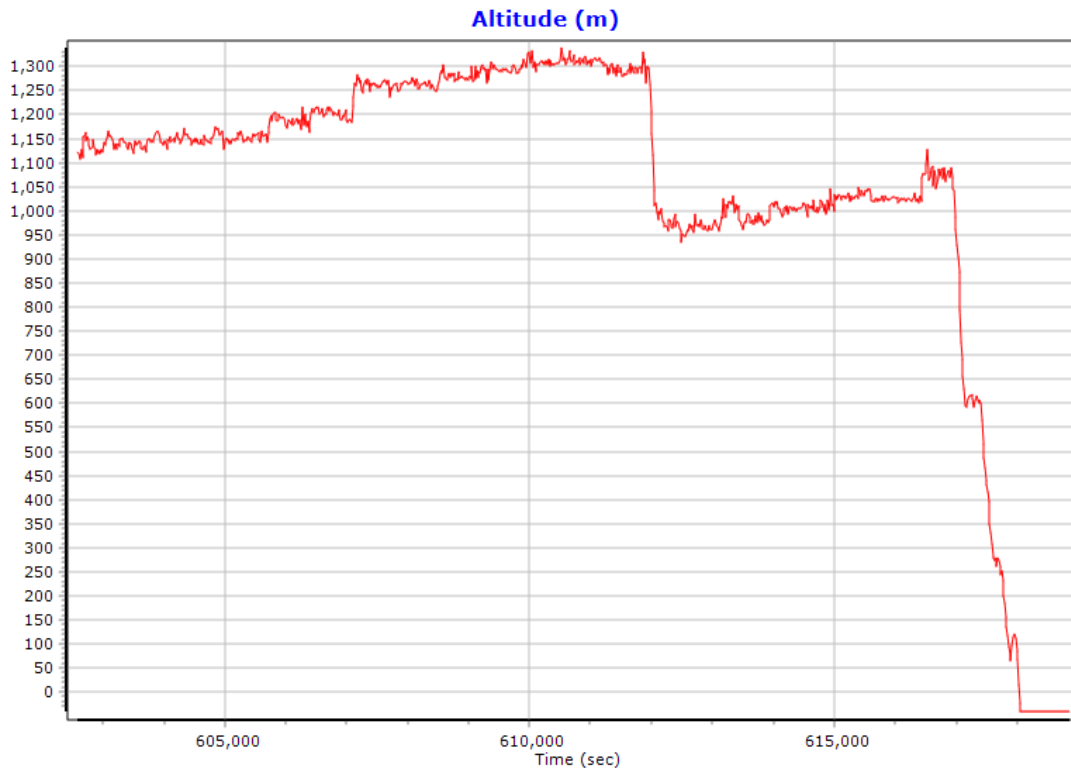
End: 5/6/2018 3:54:49 AM

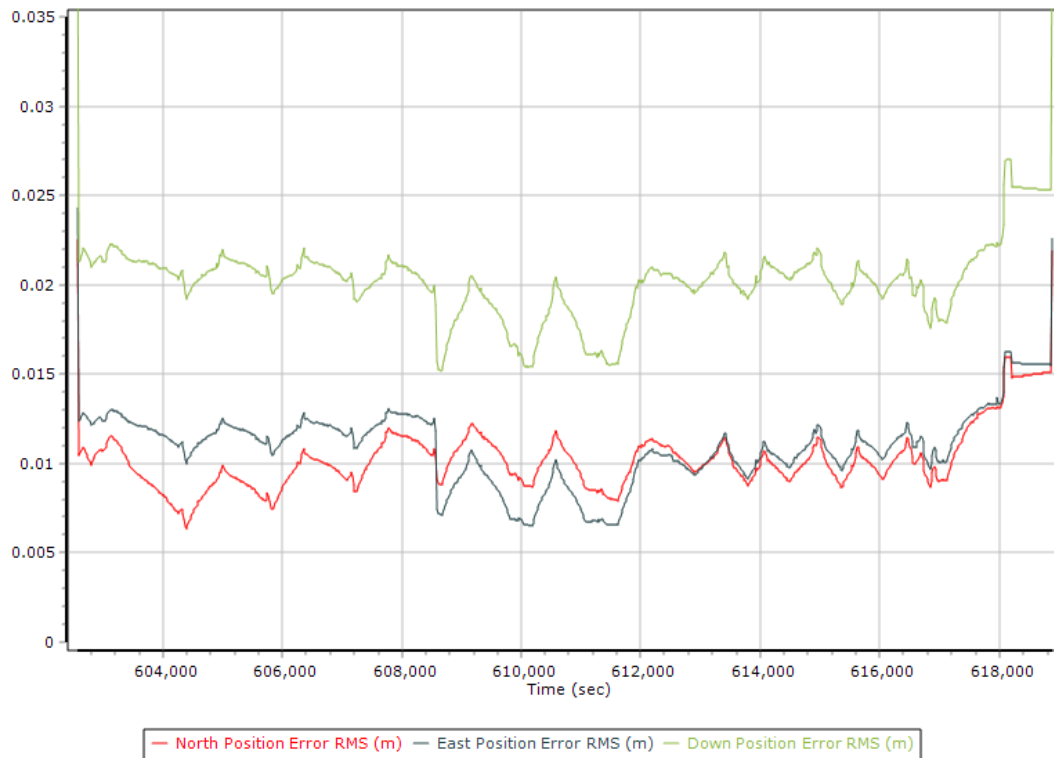
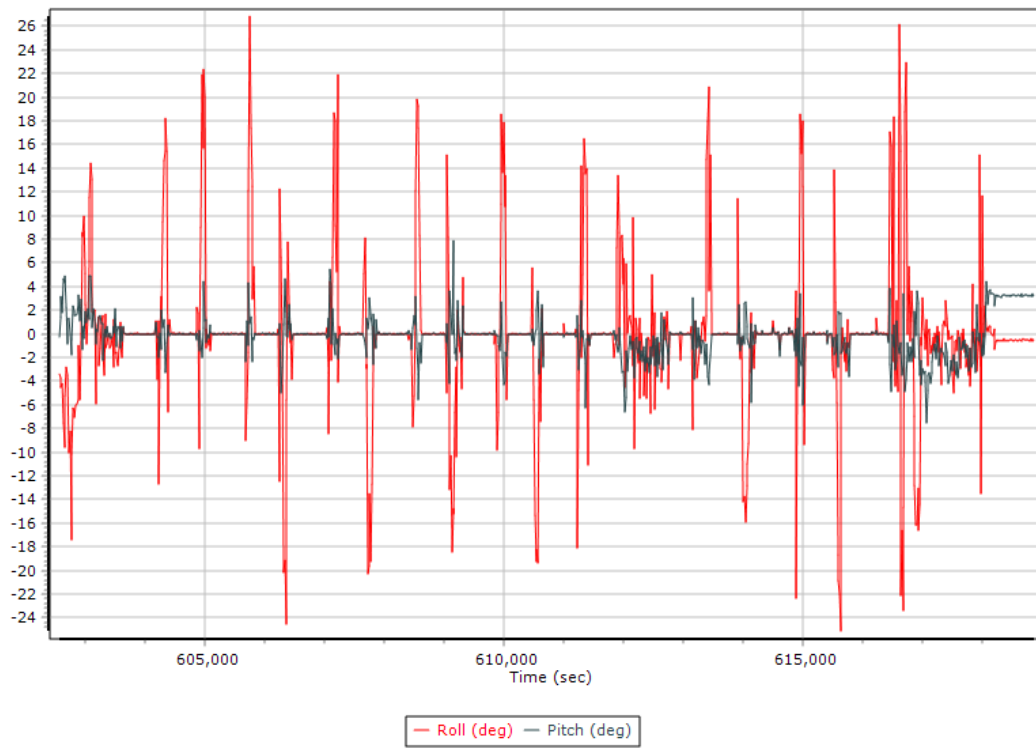
Entire time interval

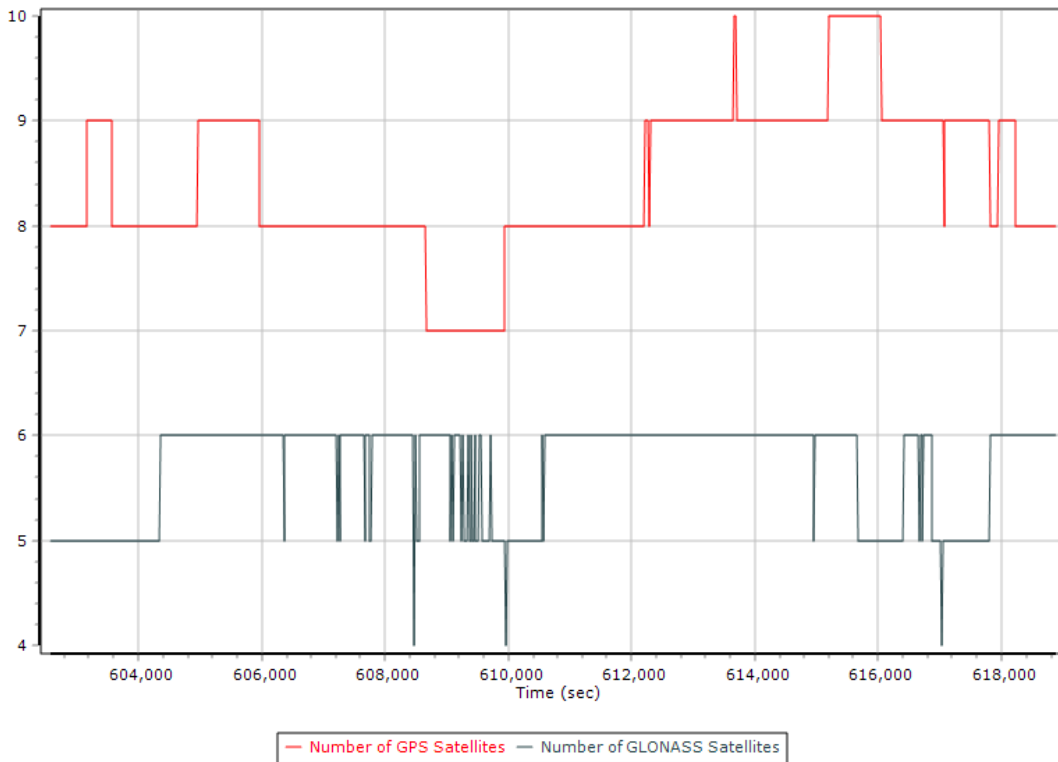
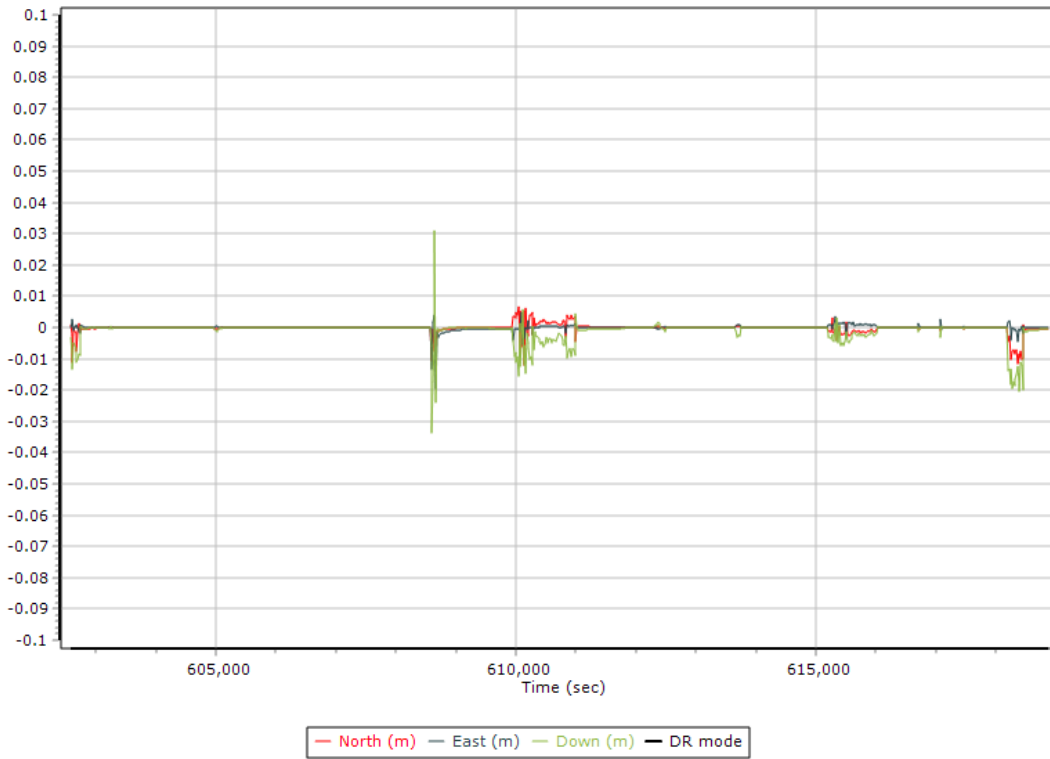
Seconds of start week

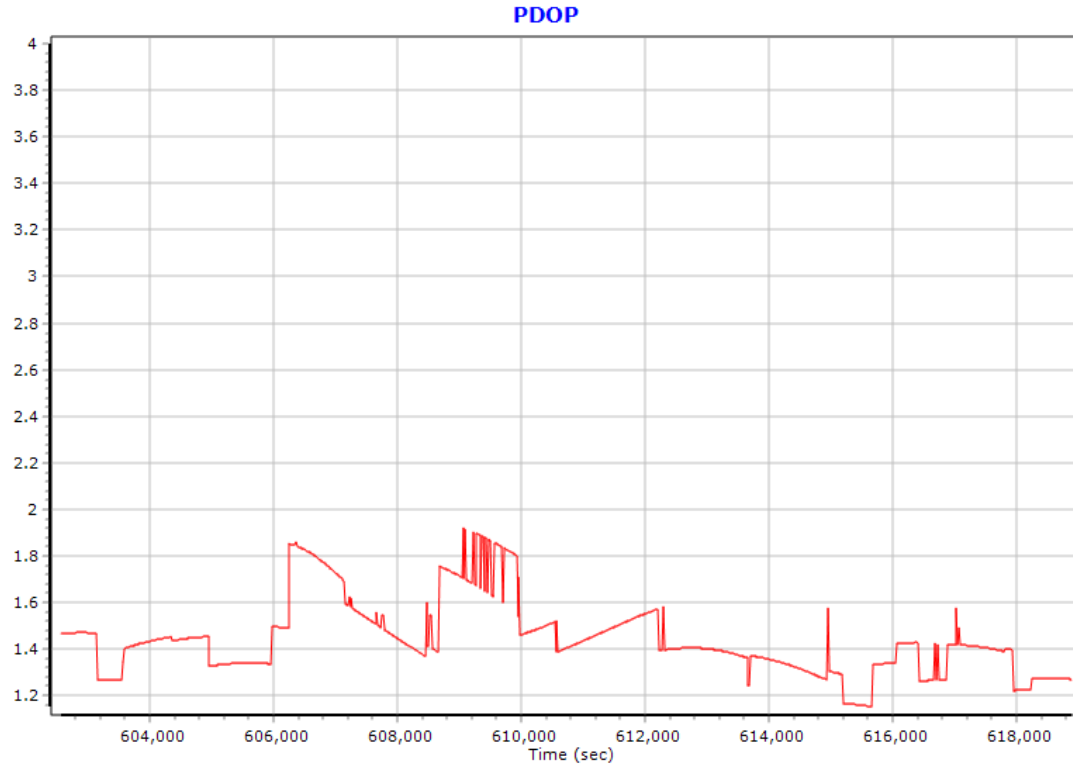
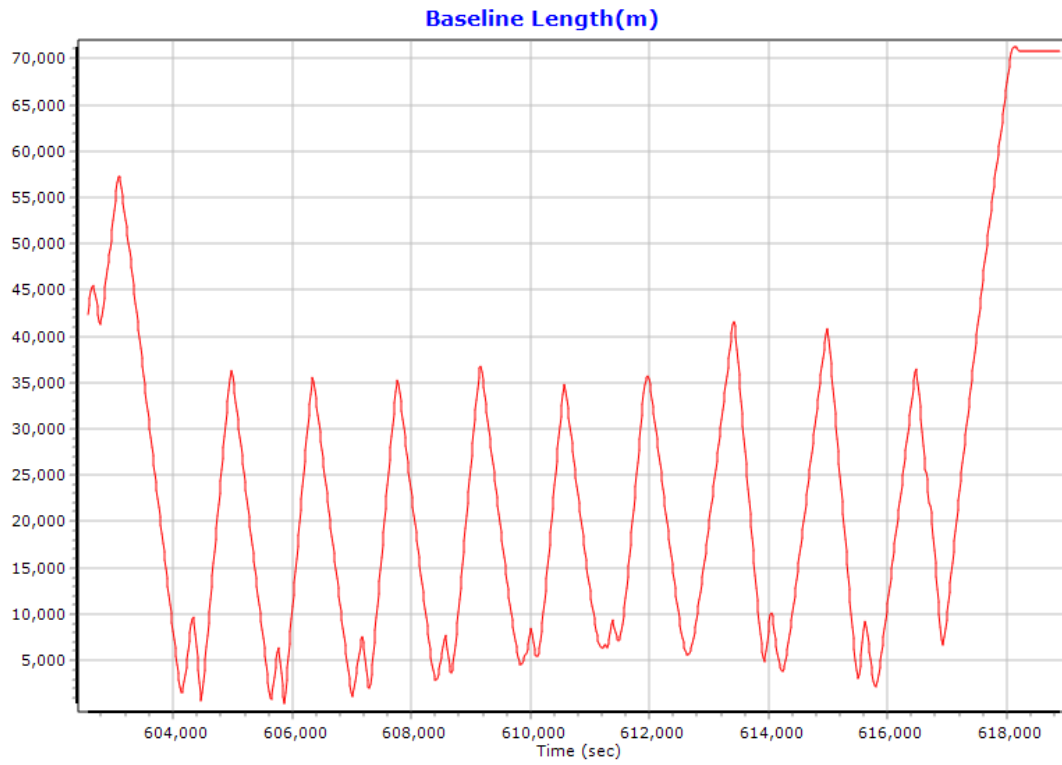
UTC Offset: 18.000

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

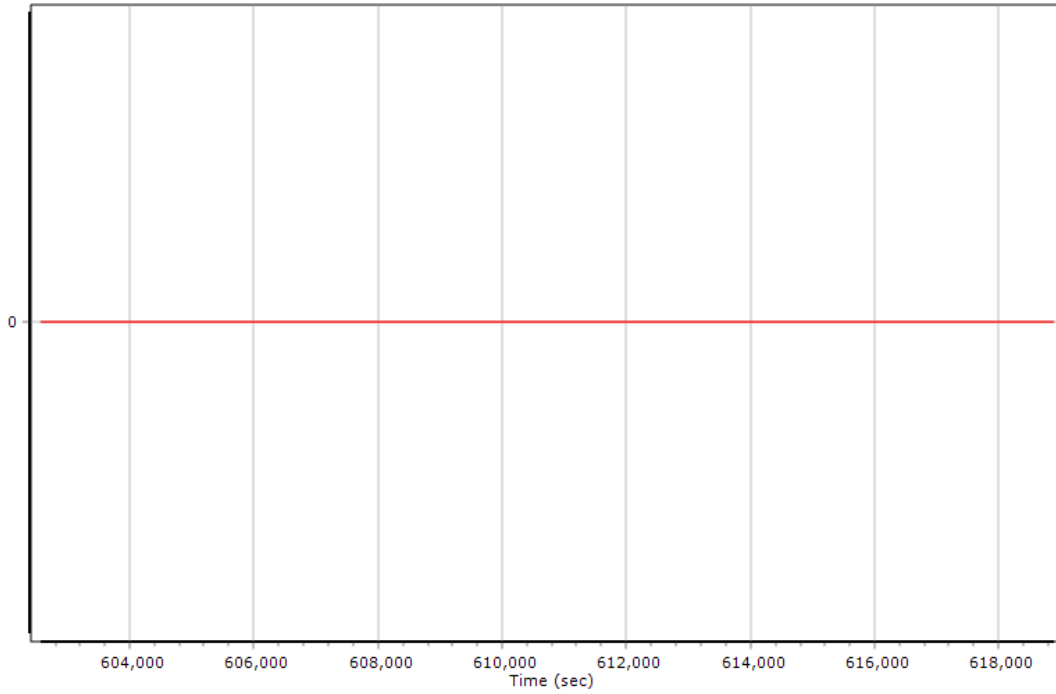






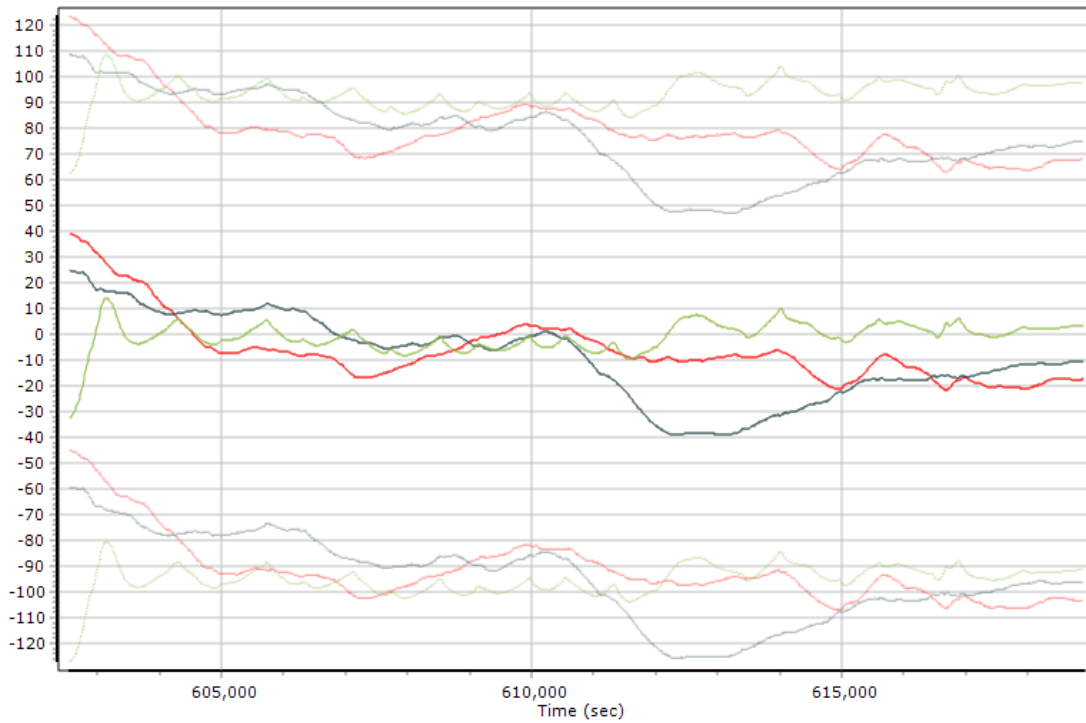


Processing Mode

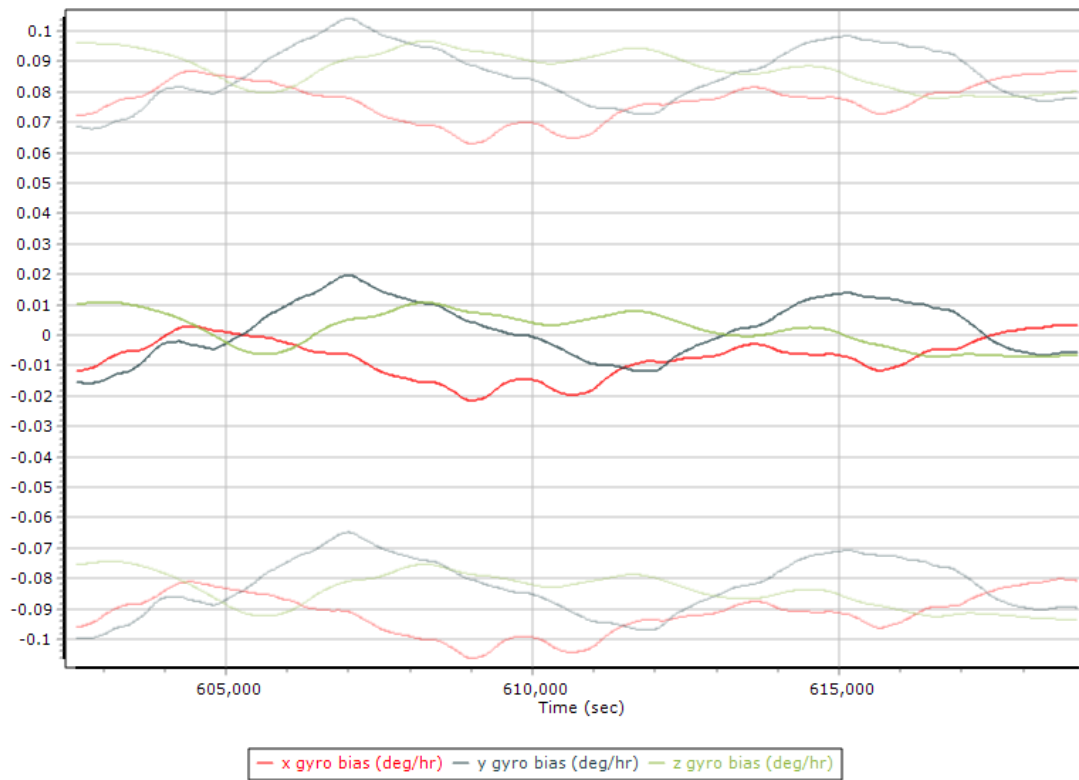
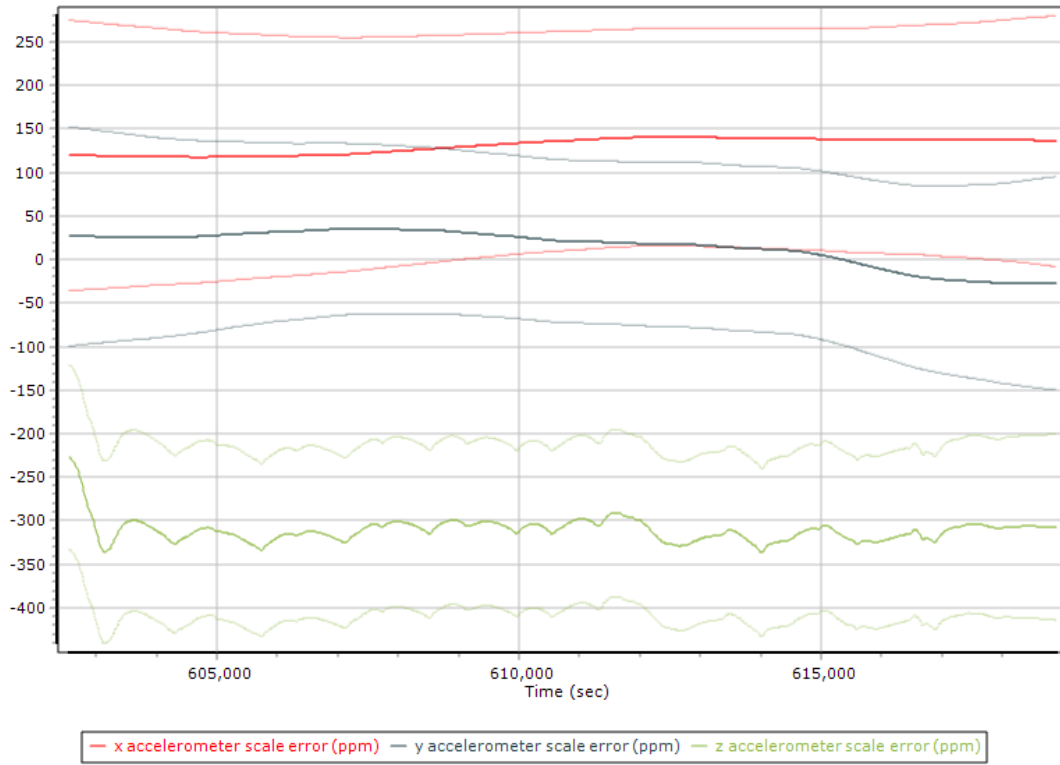


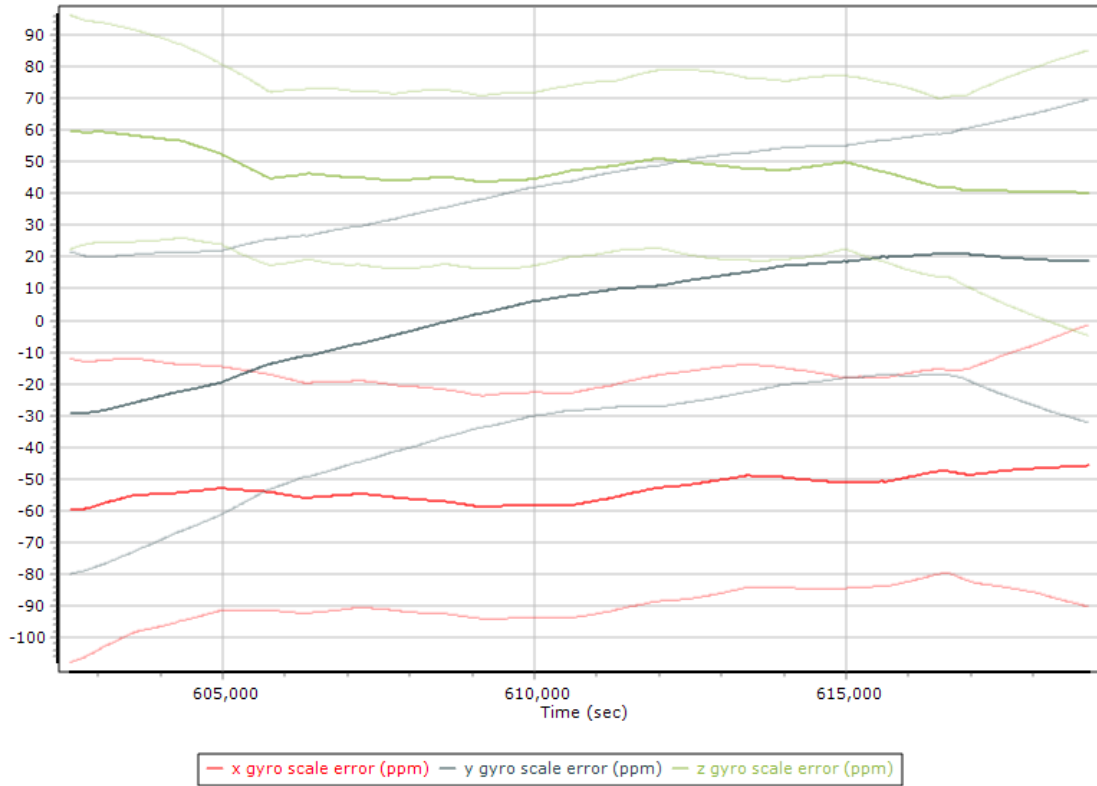
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

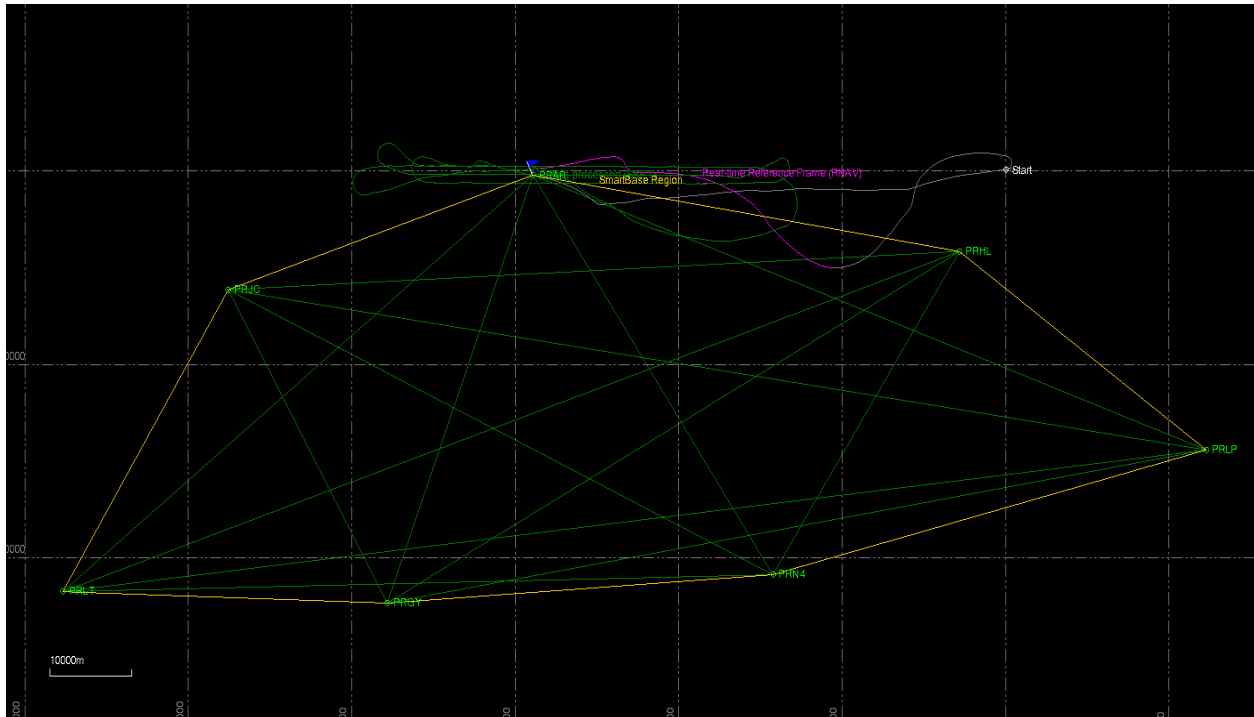


— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)





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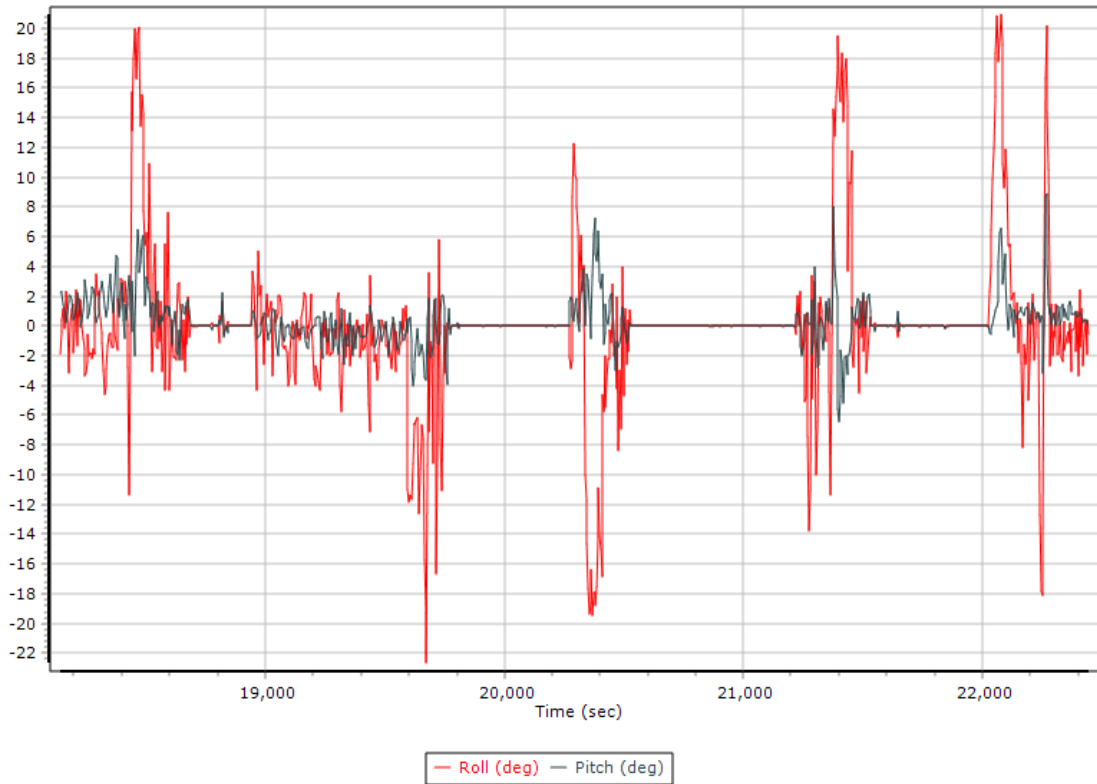
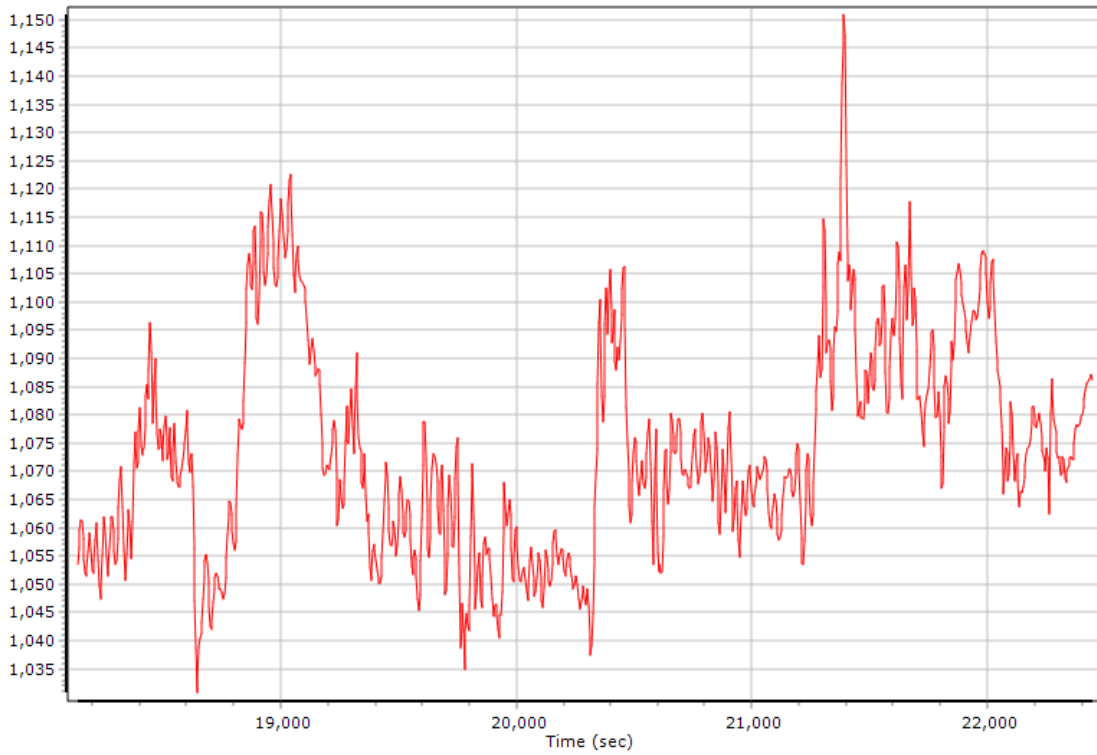


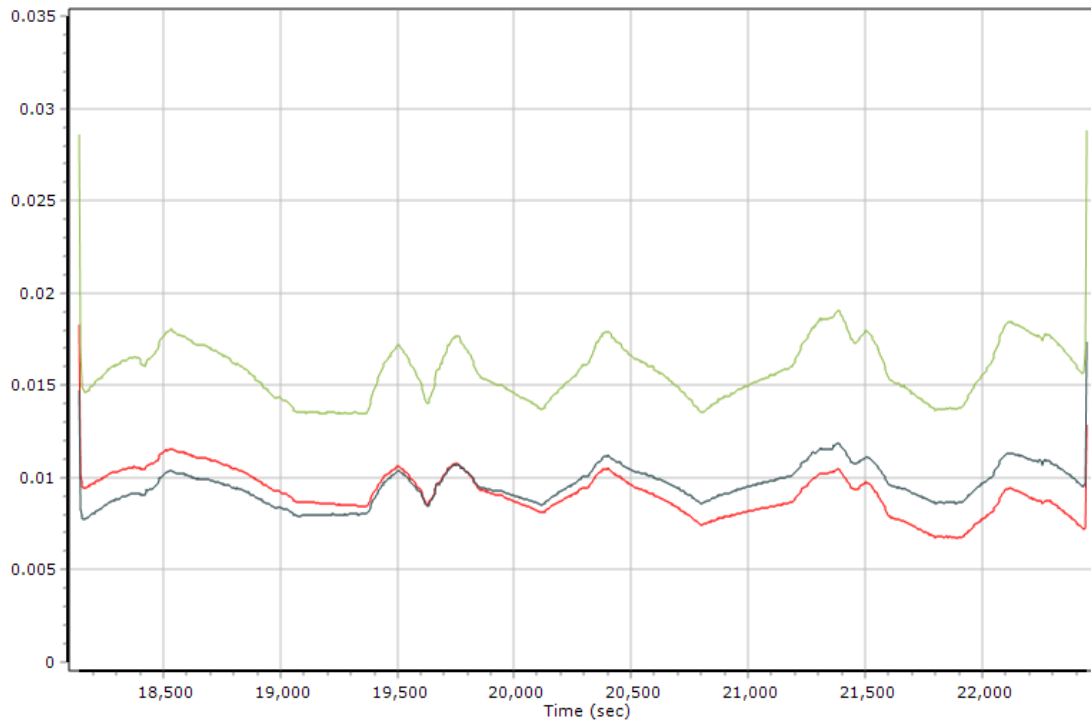
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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="3cm"/>		
	<3cm 10cm 50cm 1m 10m		

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

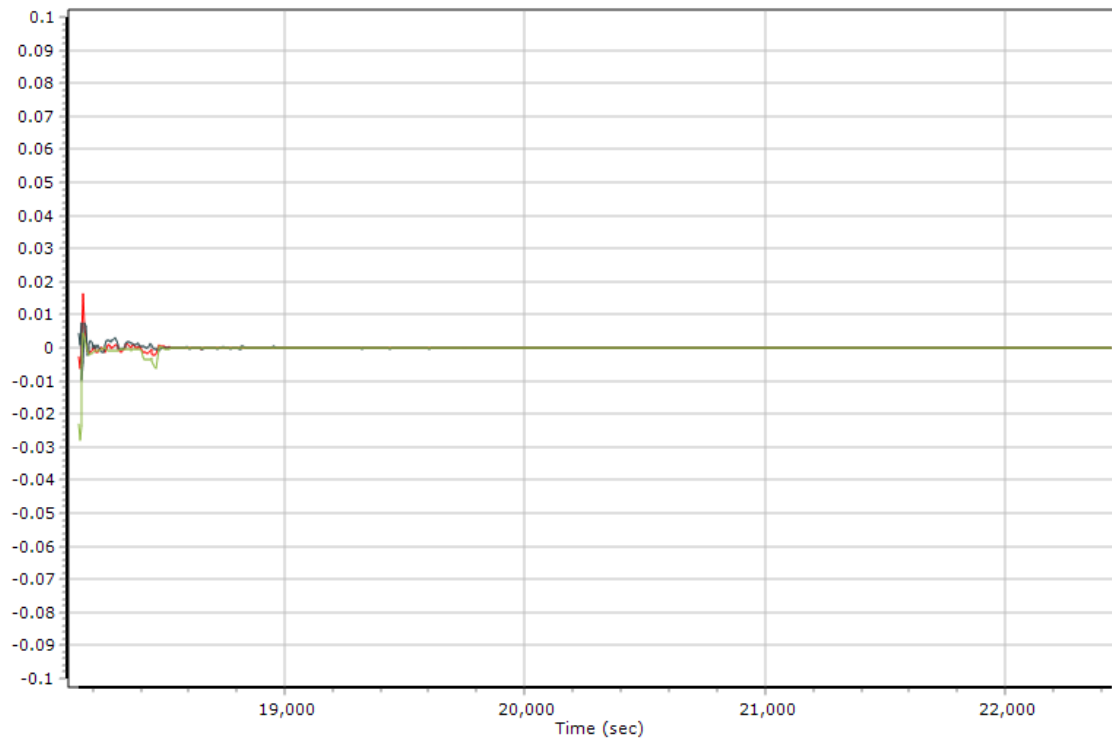
Timing	
Start	<input type="text" value="5/6/2018 4:53:17 AM"/>
End	<input type="text" value="5/6/2018 6:14:09 AM"/>
<input type="checkbox"/>	Entire time interval
<input type="checkbox"/>	Seconds of start week
UTC Offset	<input type="text" value="18.000"/>
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

Altitude (m)

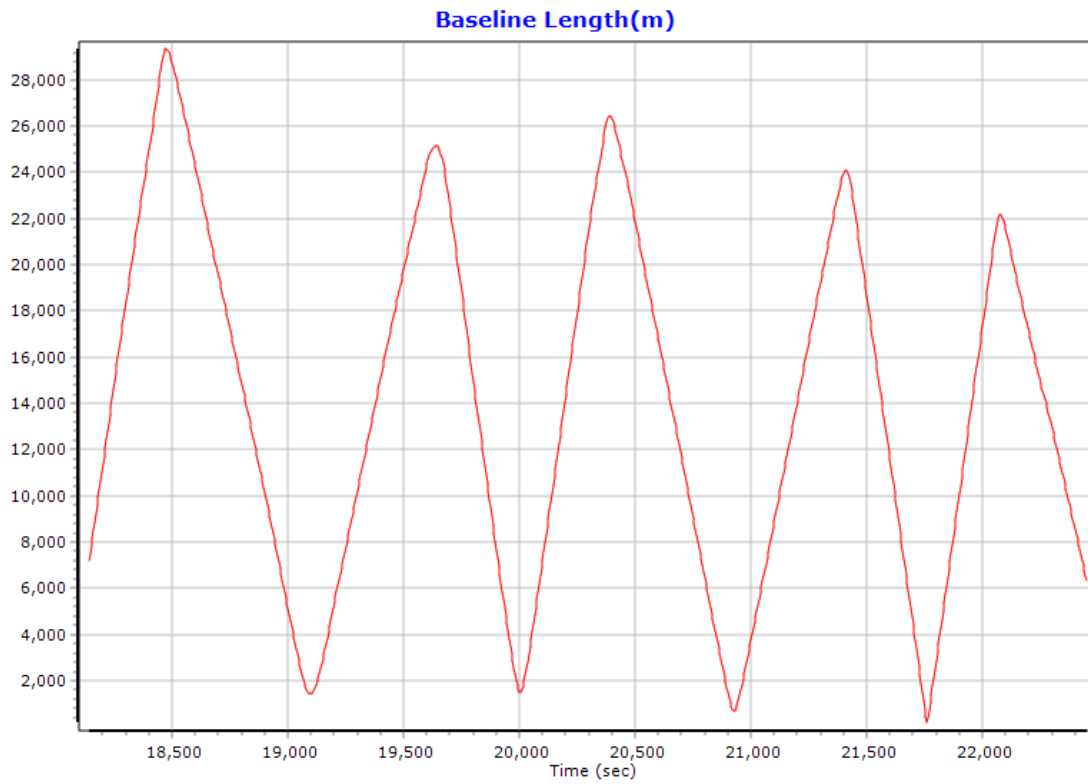
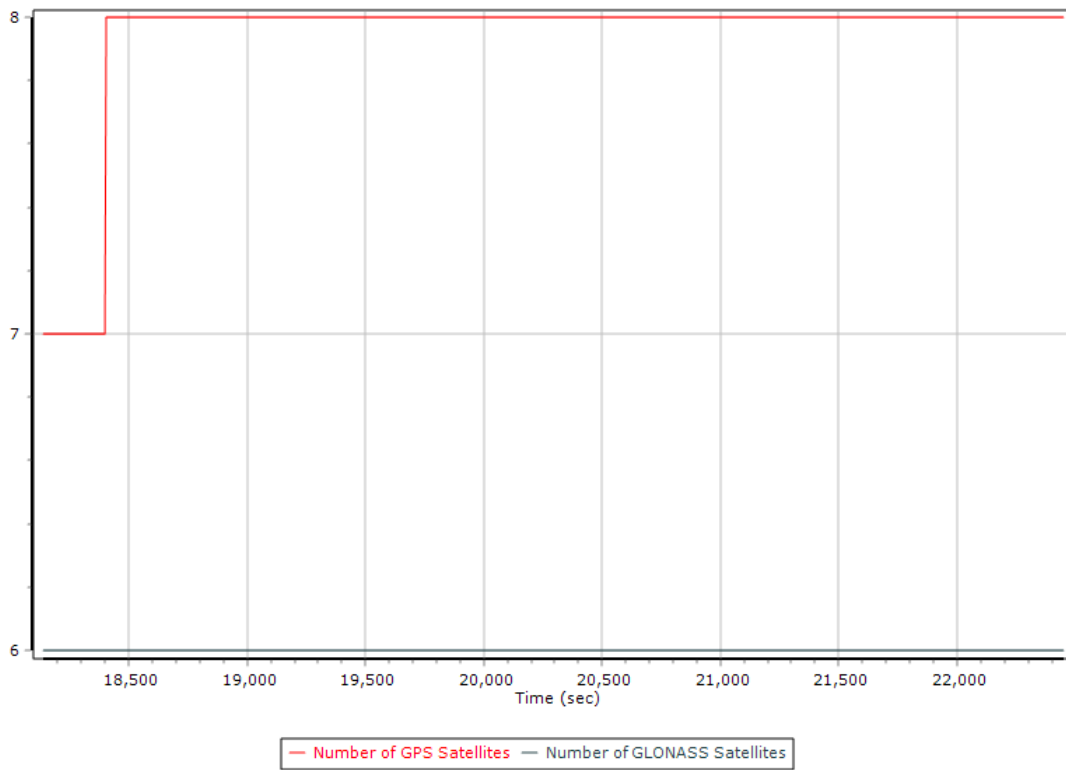




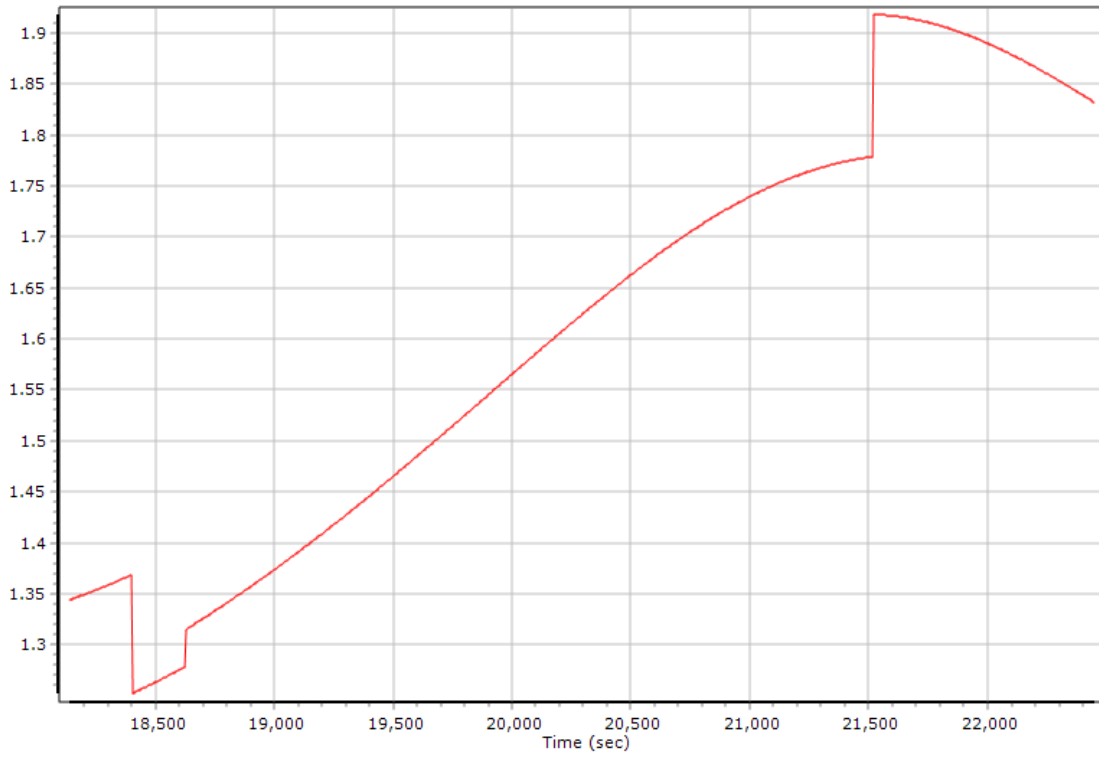
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



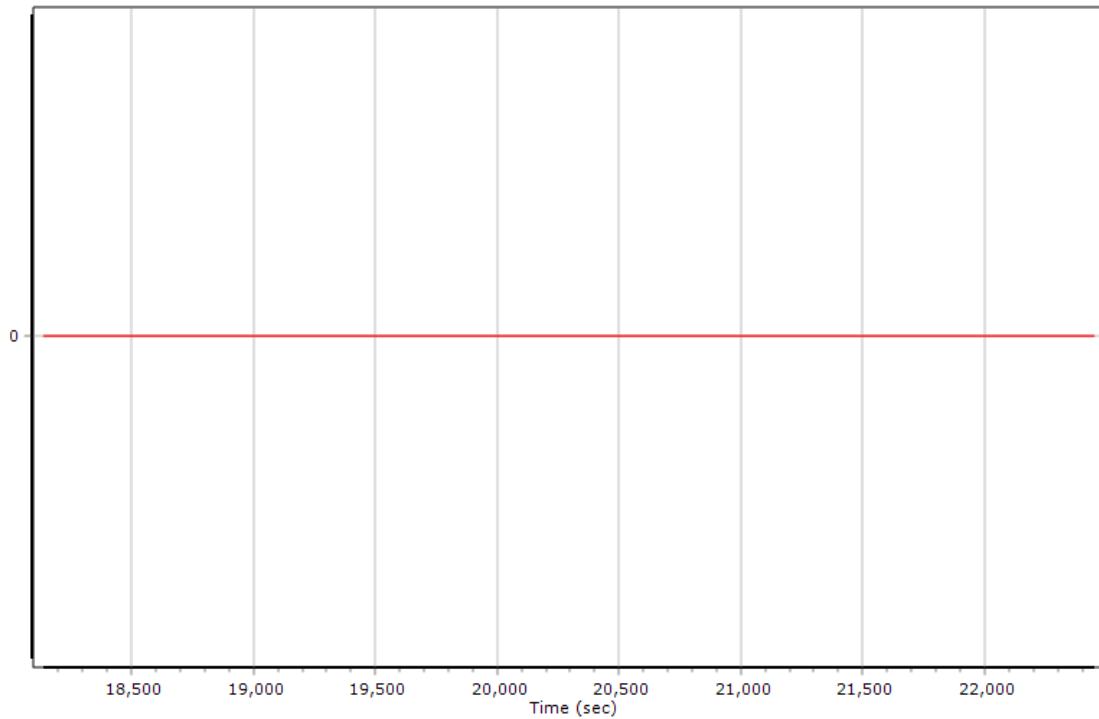
— North (m) — East (m) — Down (m) — DR mode



PDOP

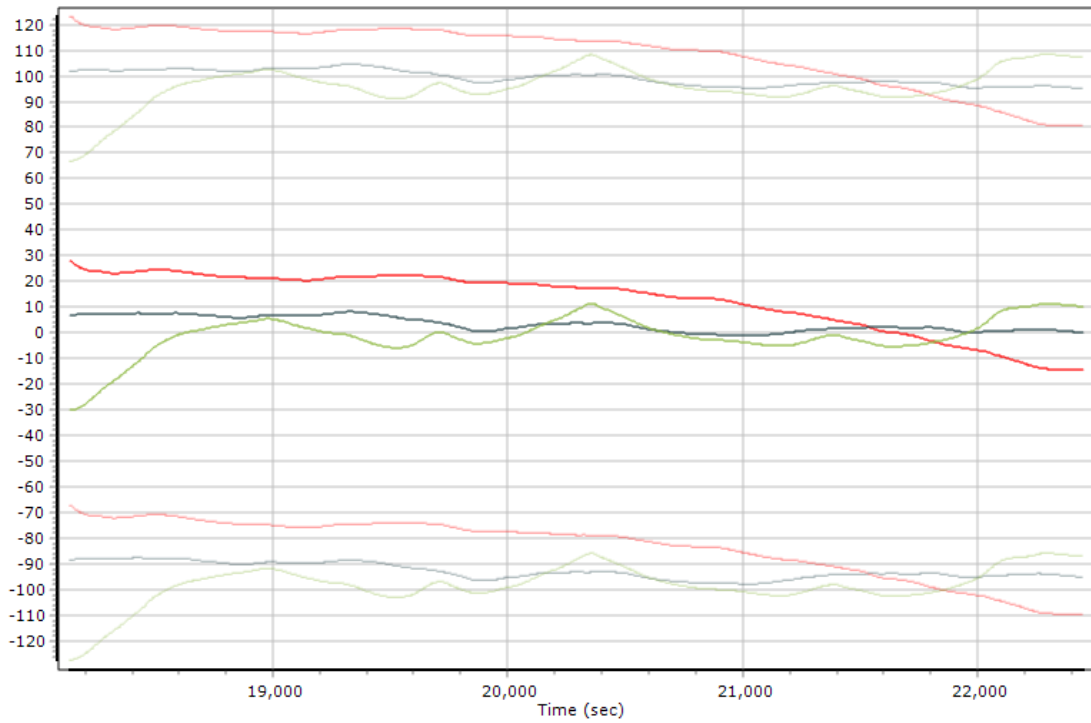


Processing Mode

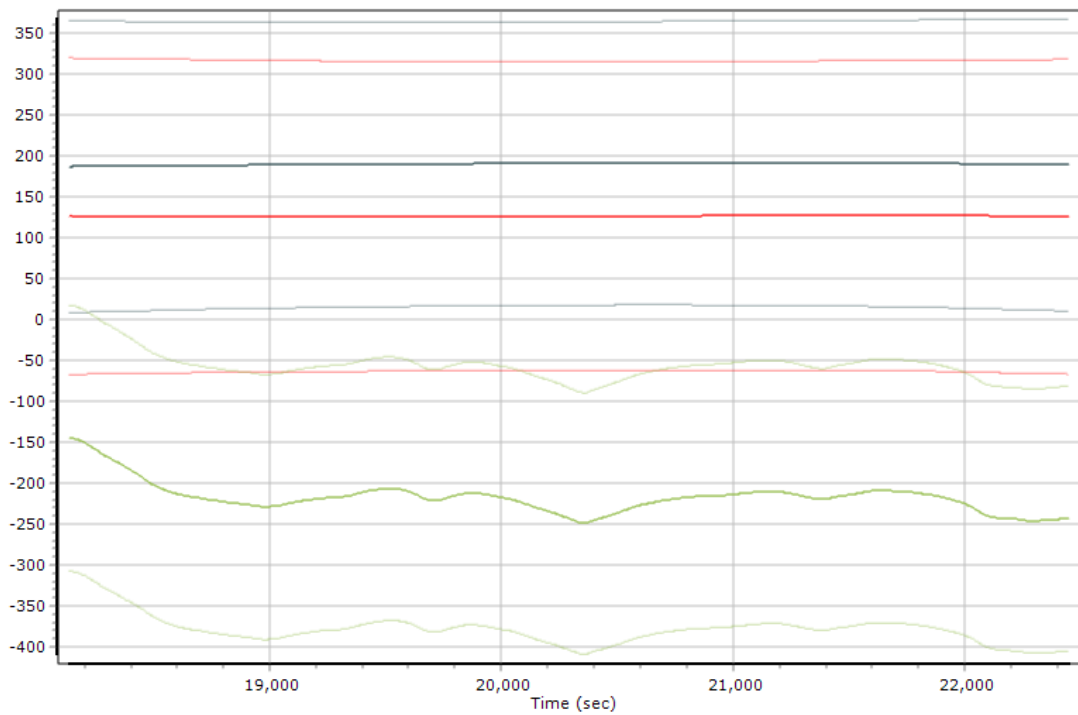


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

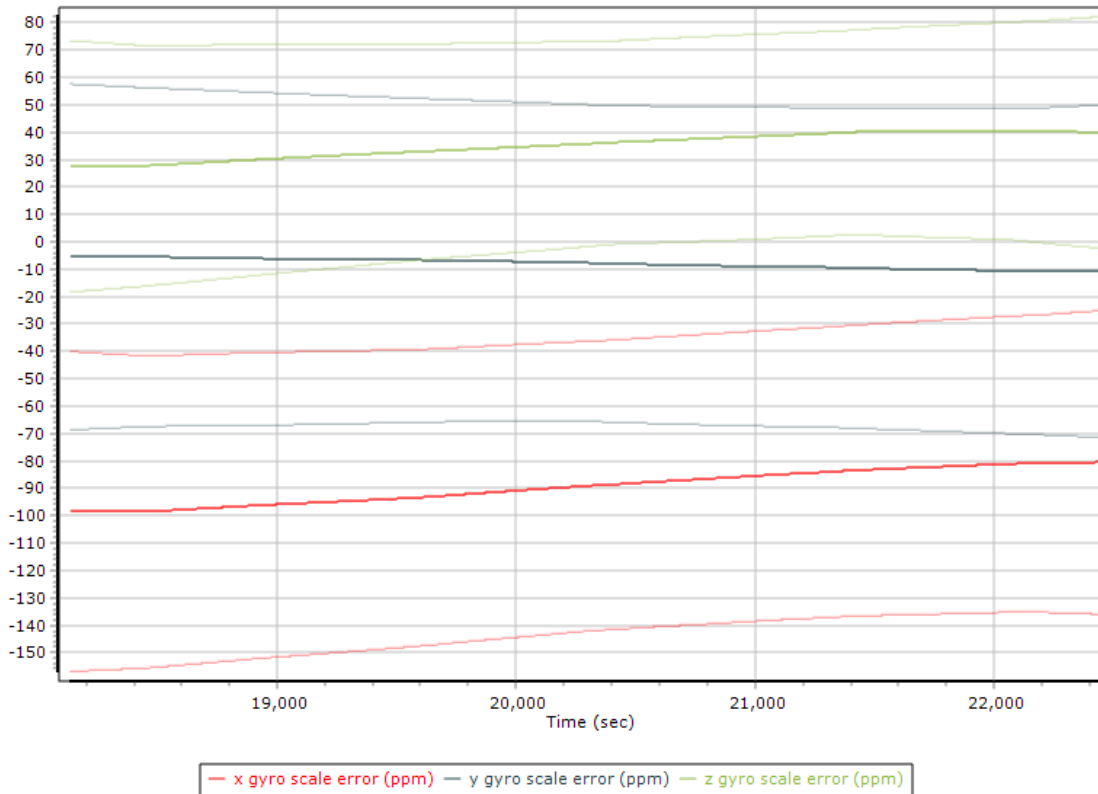
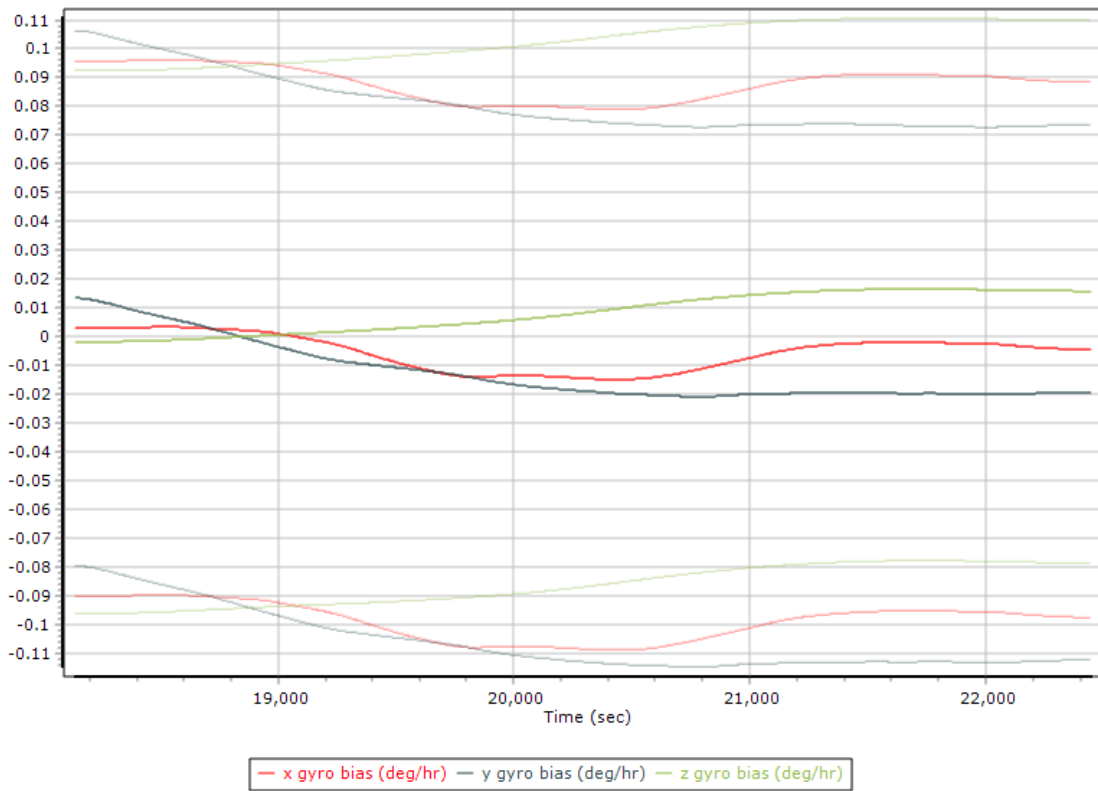
Sensor Errors



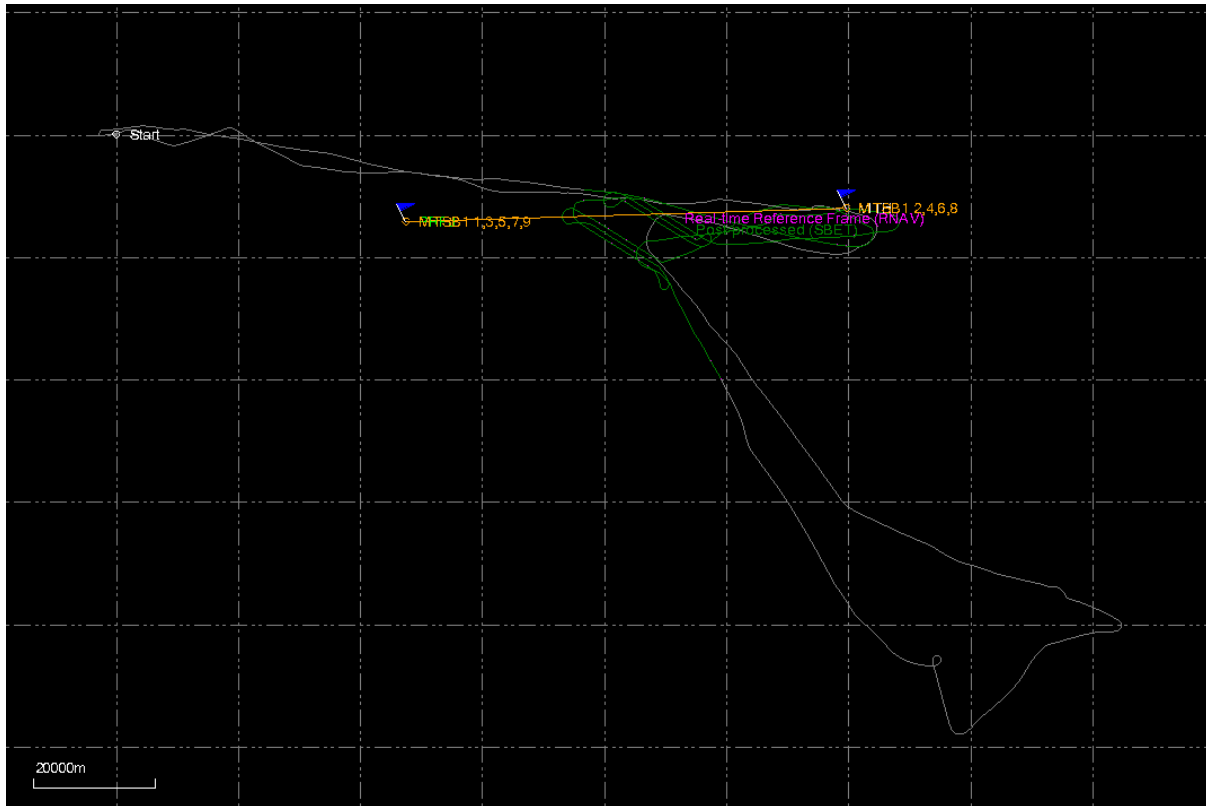
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)



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



AZT18126B



Project Settings

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

Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.049 m	0.003 m	-1.230 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	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



Timing

Start

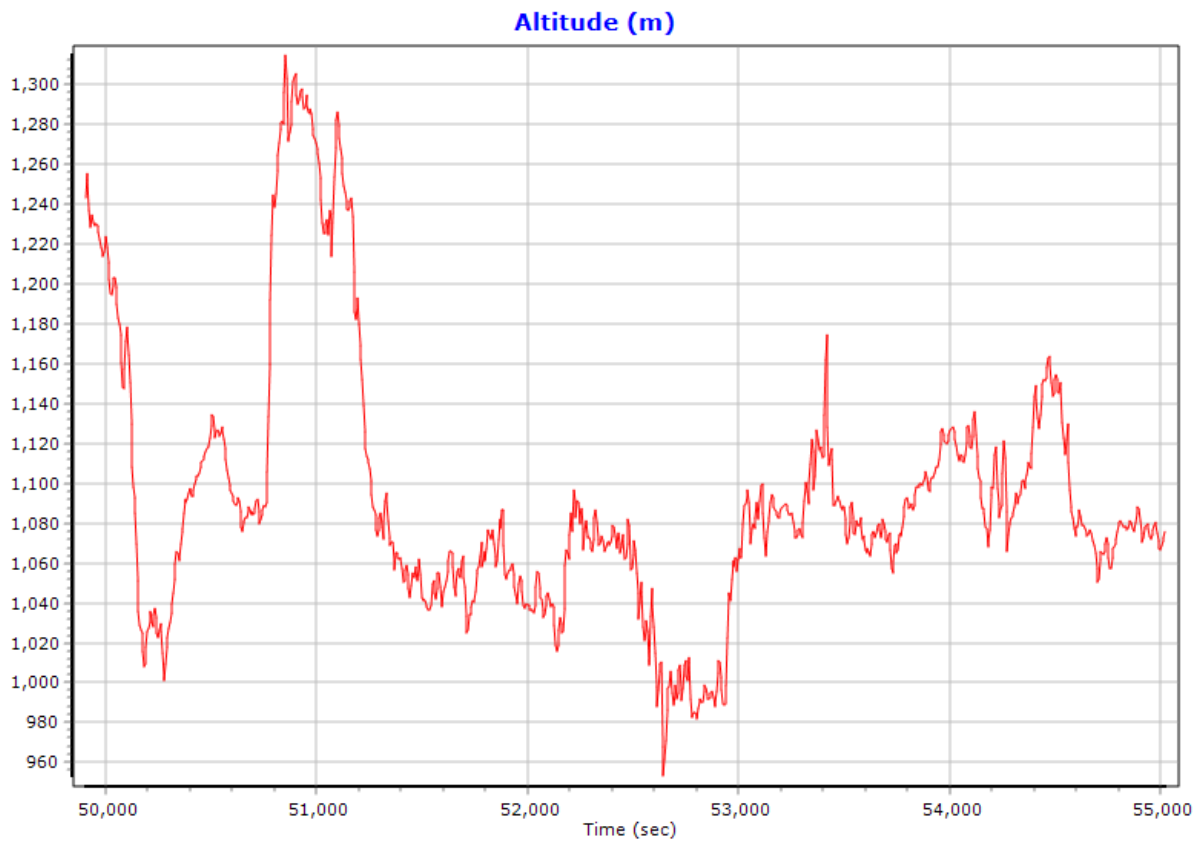
End

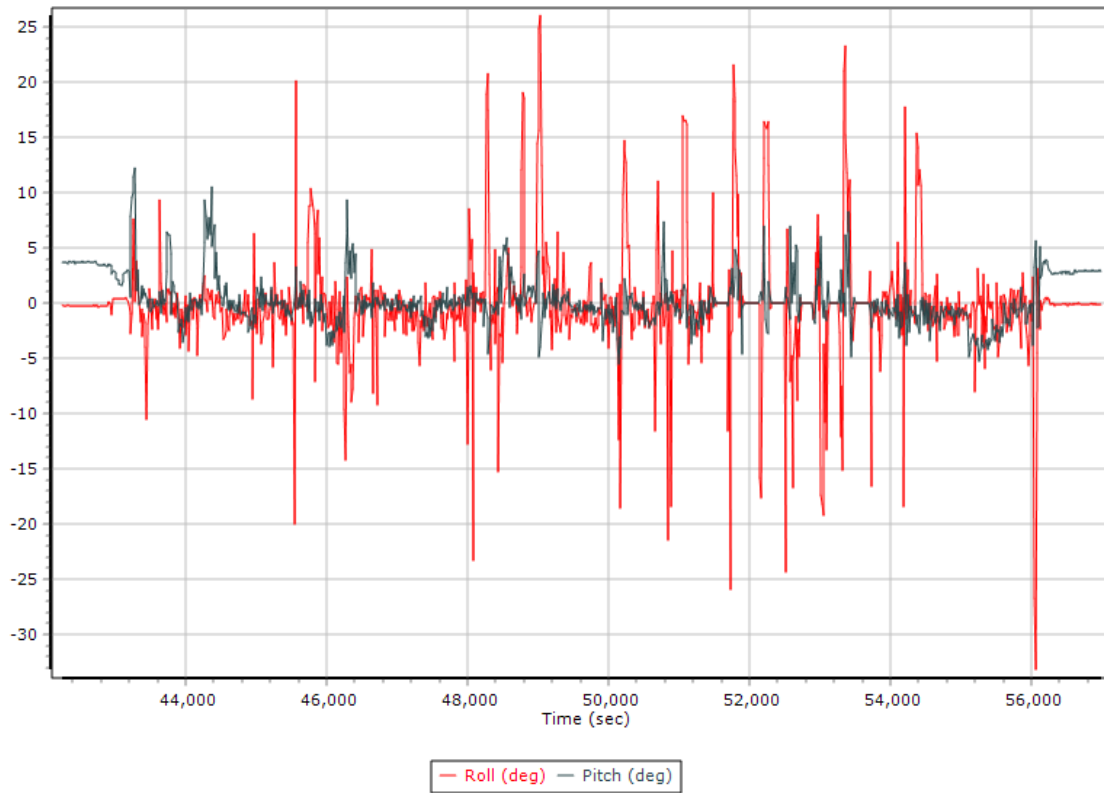
Entire time interval

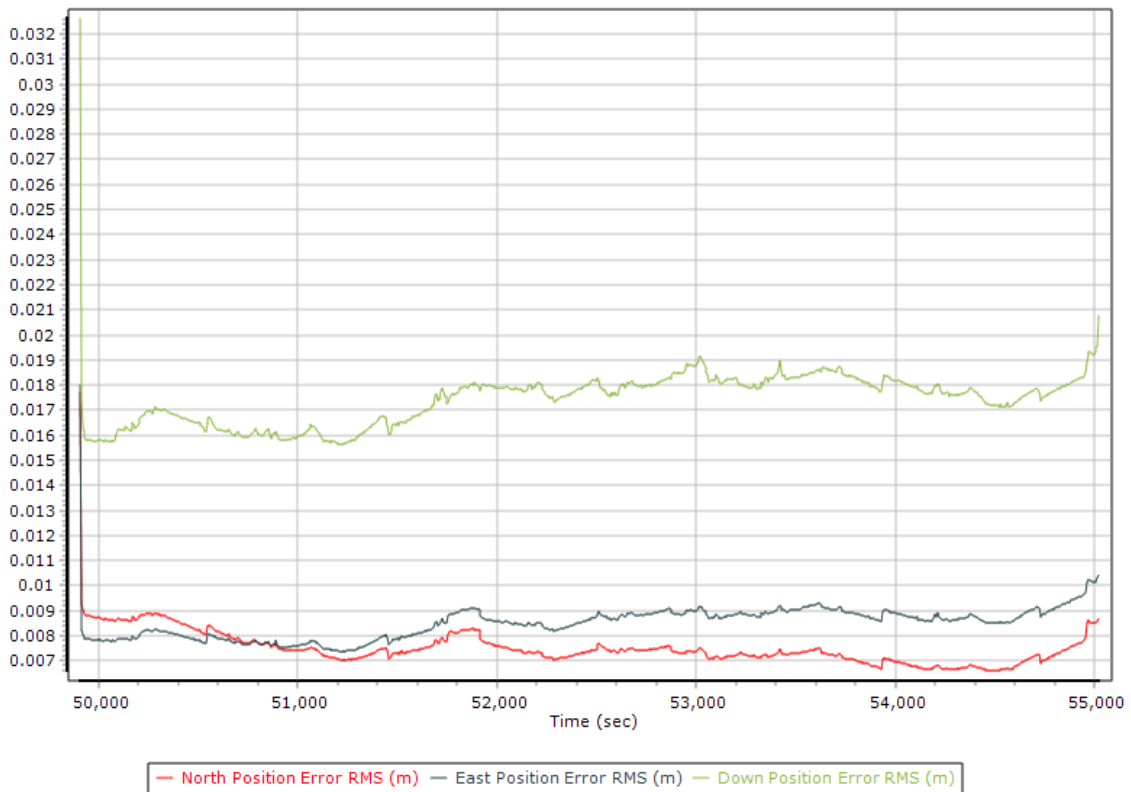
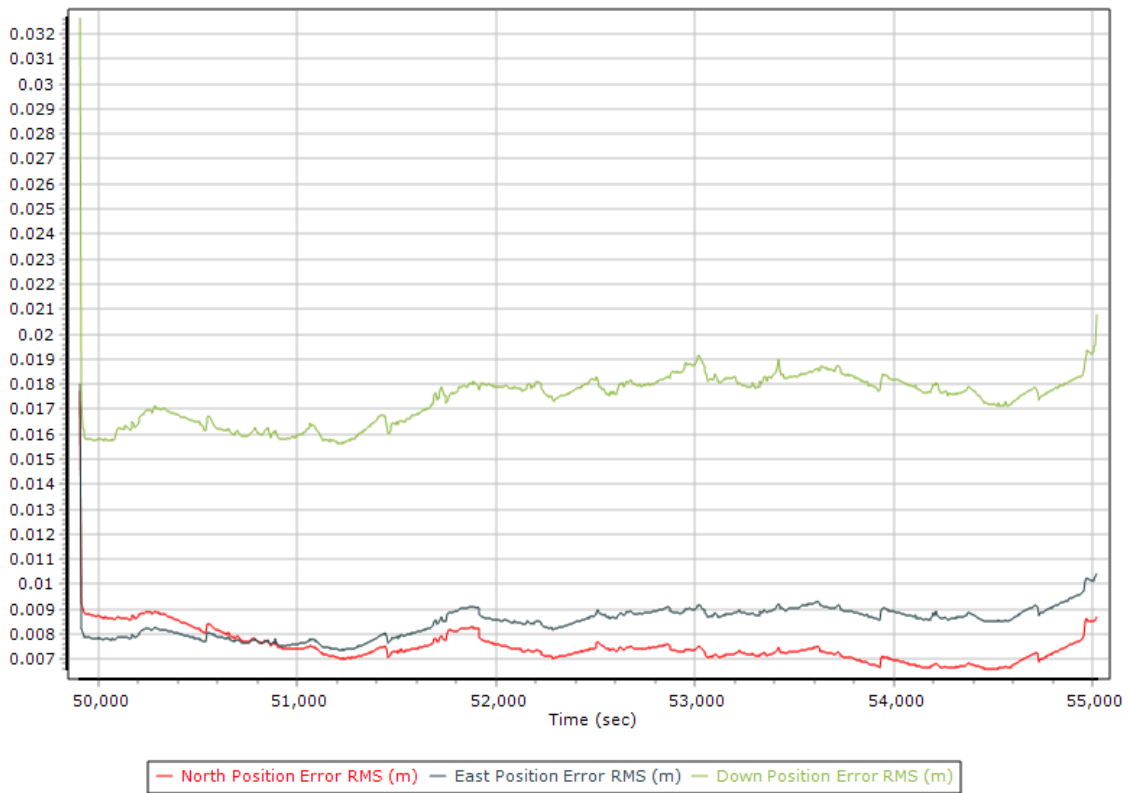
Seconds of start week

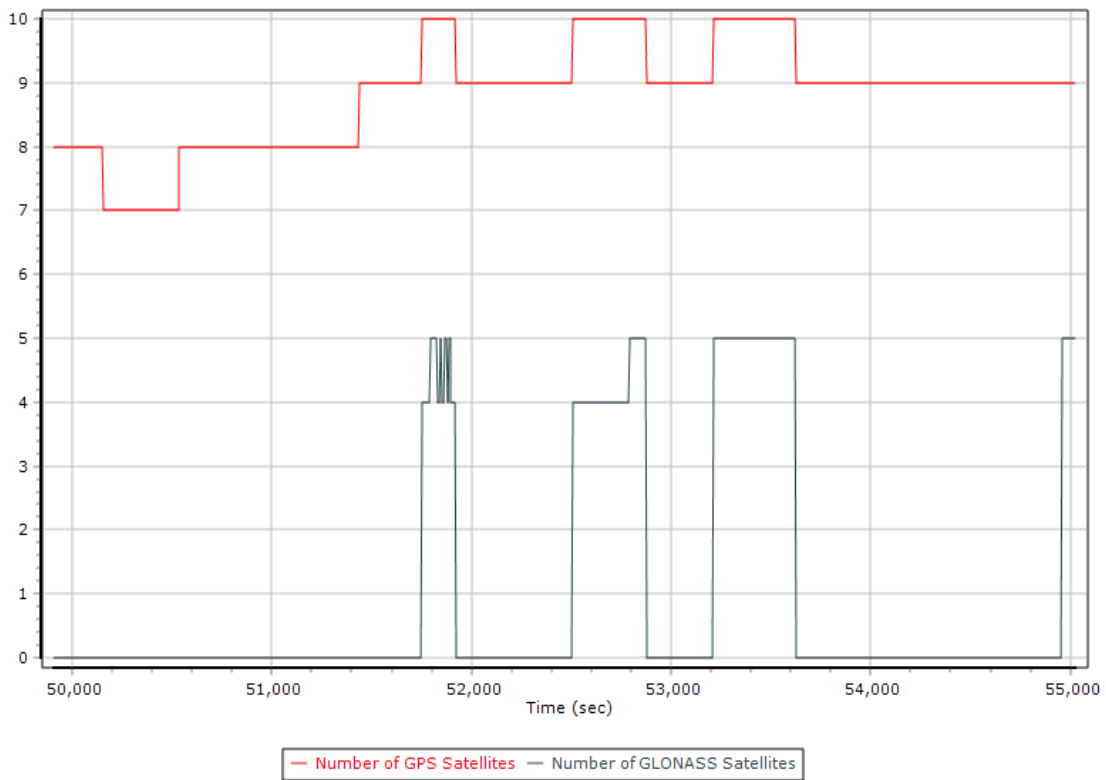
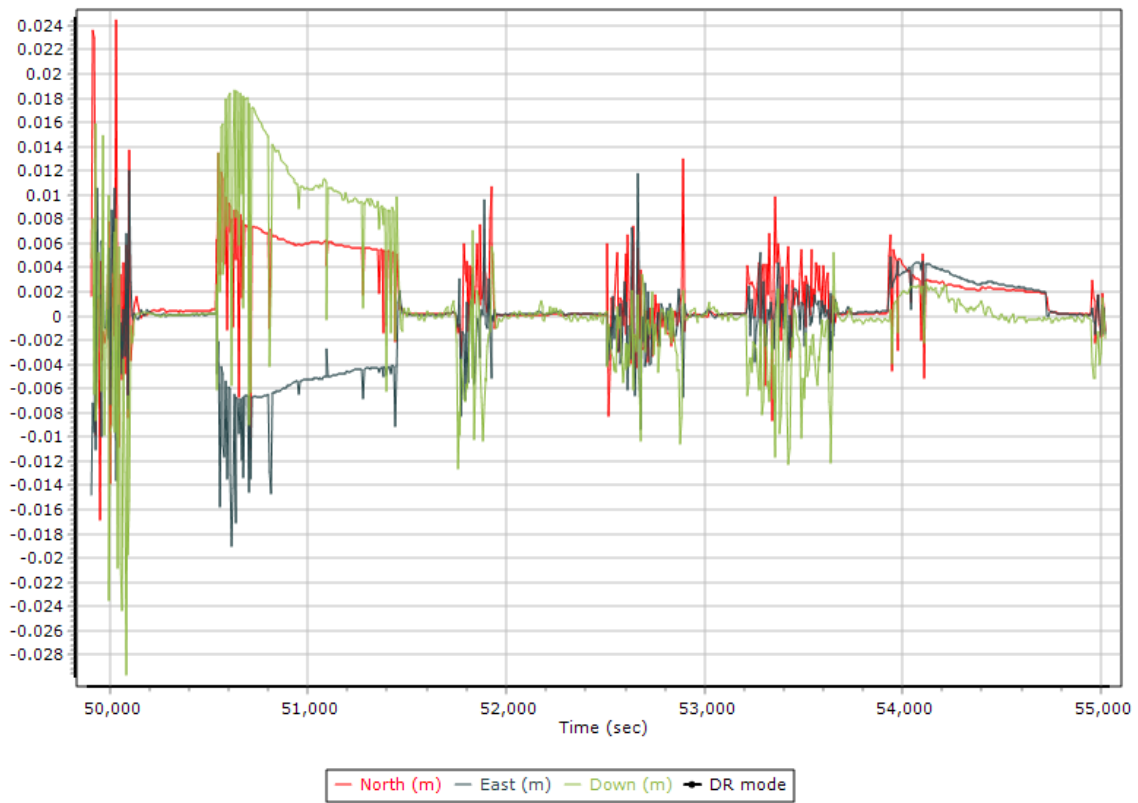
UTC Offset

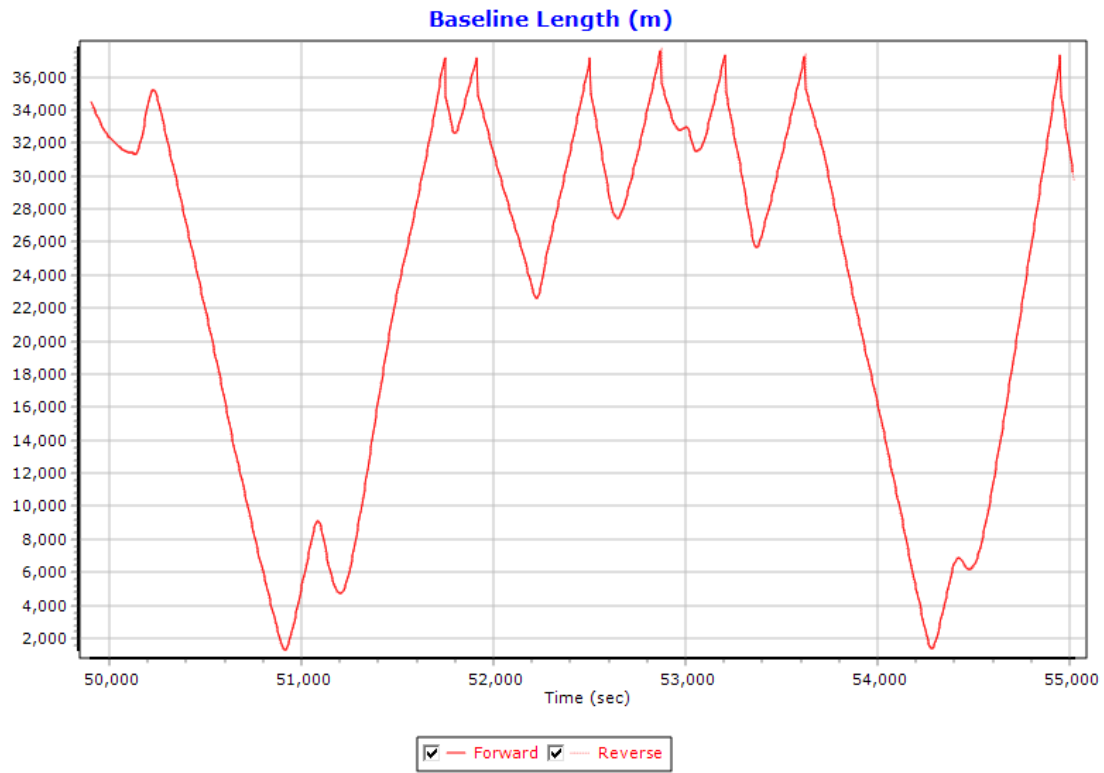
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

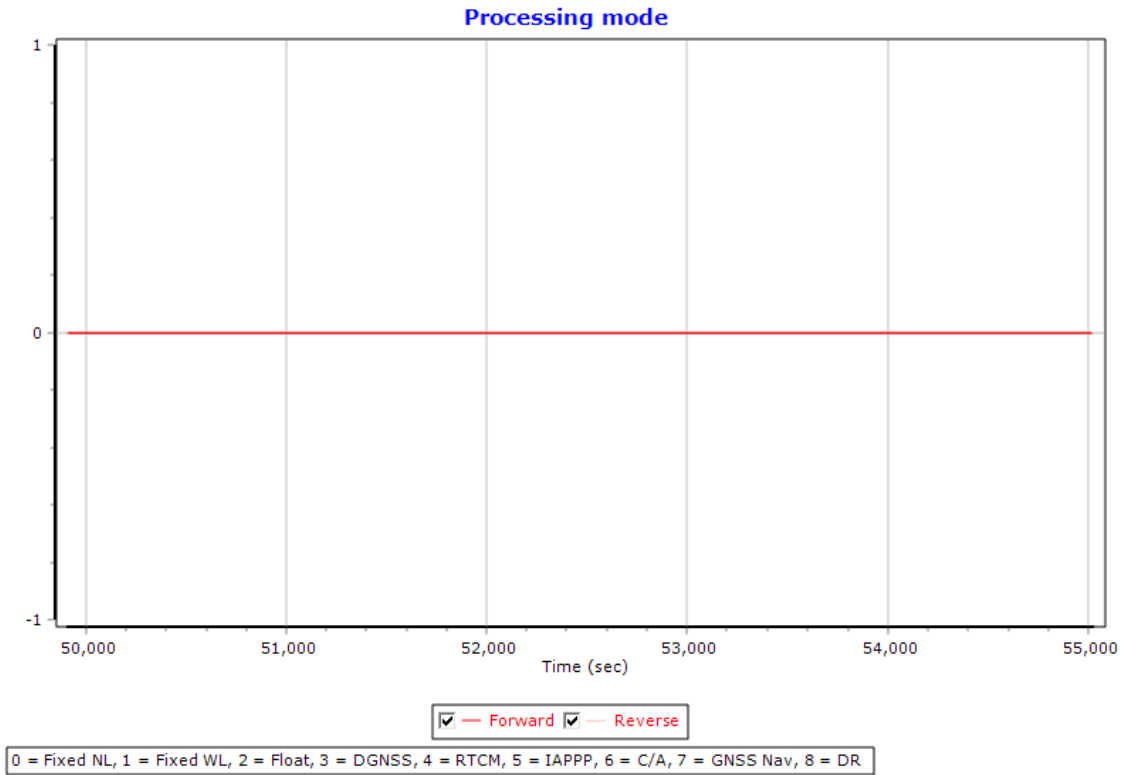




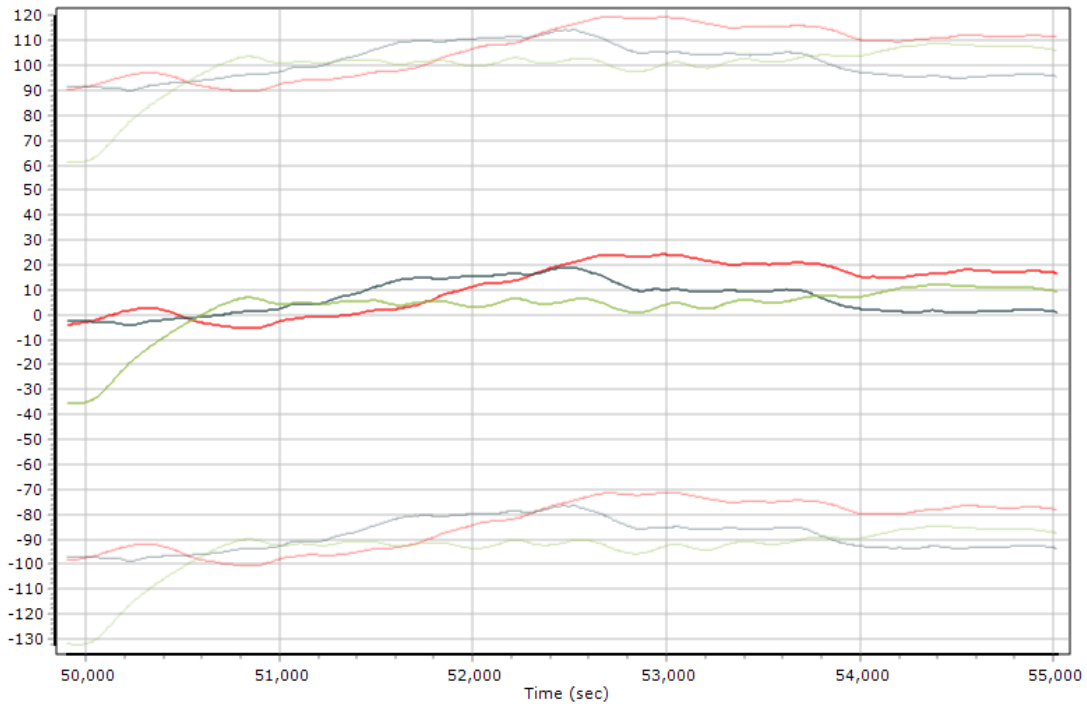




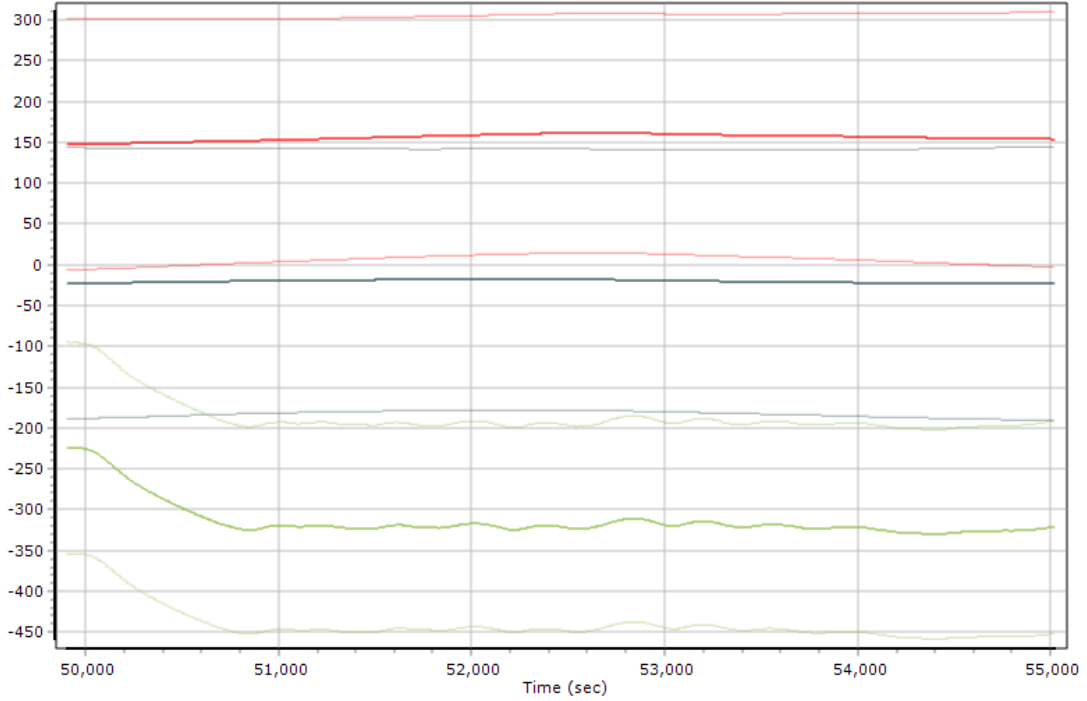




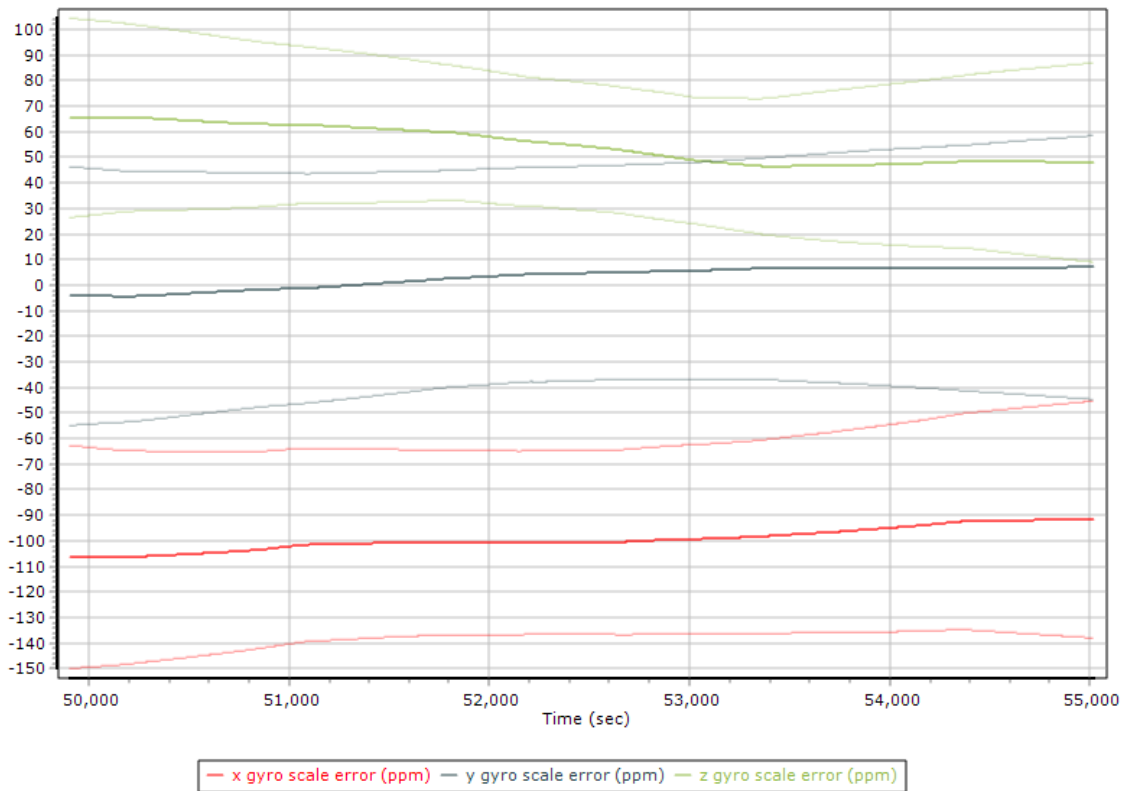
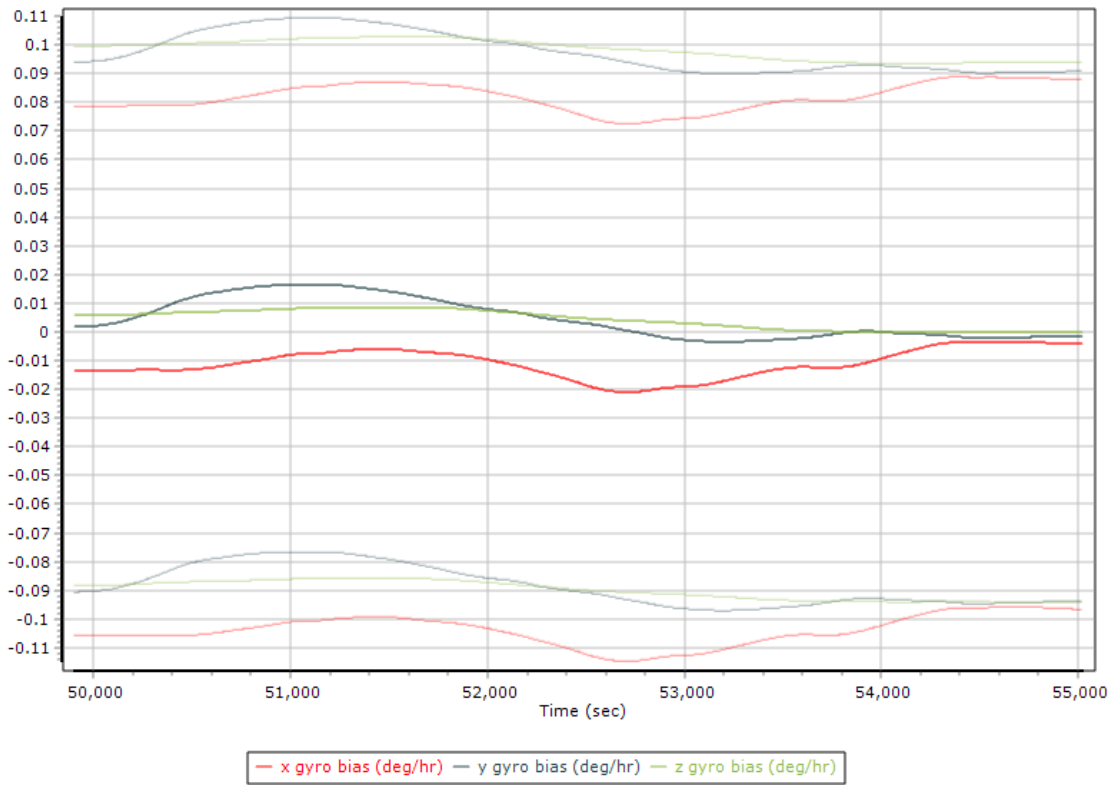
Sensor Errors



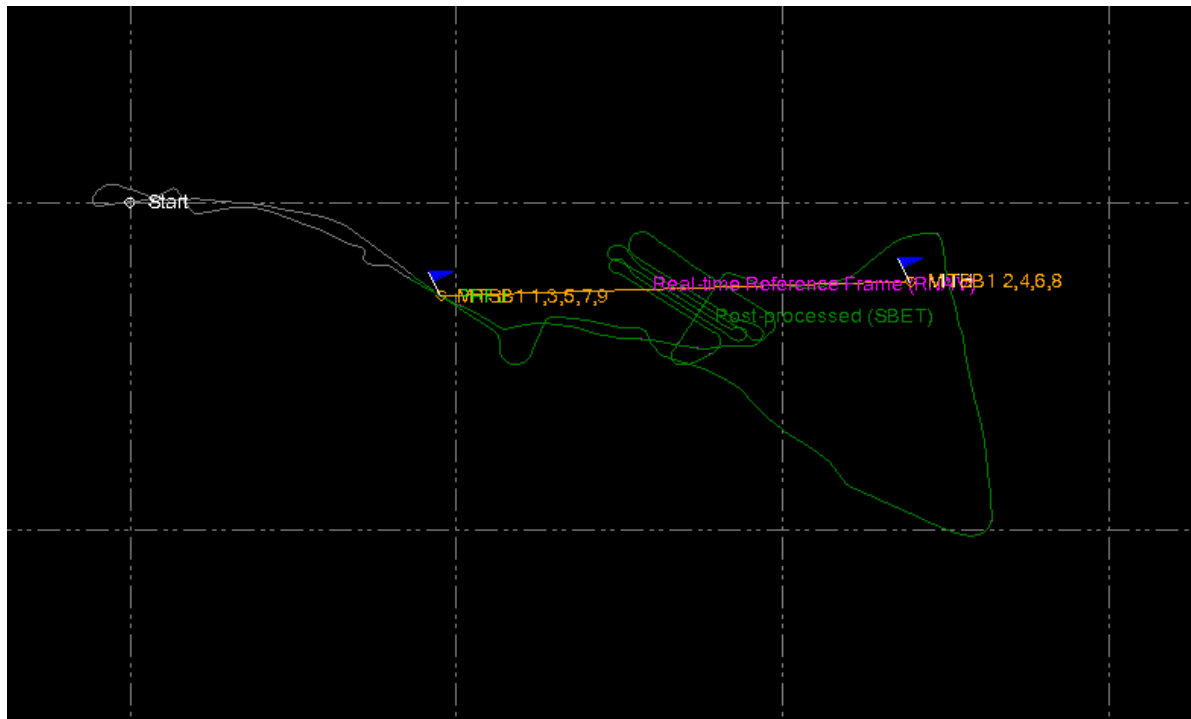
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)



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



AZT18126C



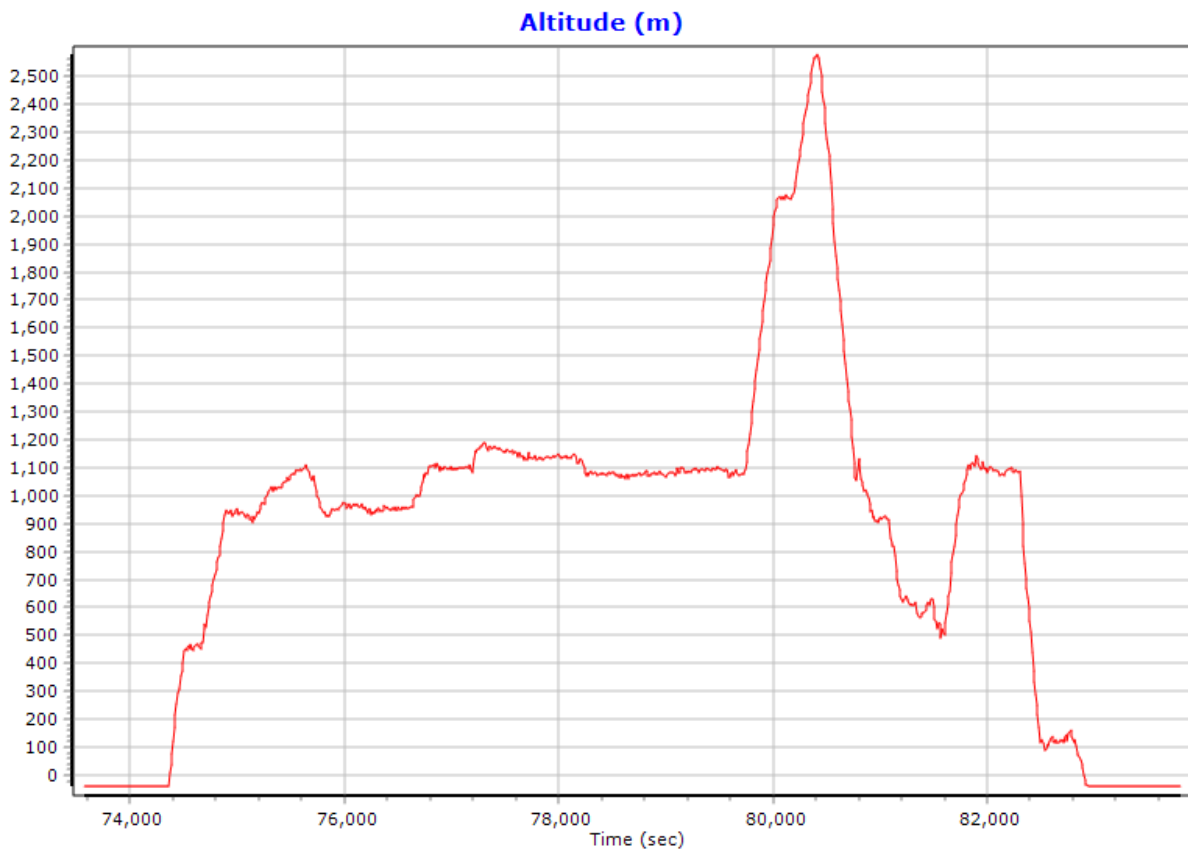
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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="0.3"/>		
	<3cm 10cm 50cm 1m 10m		

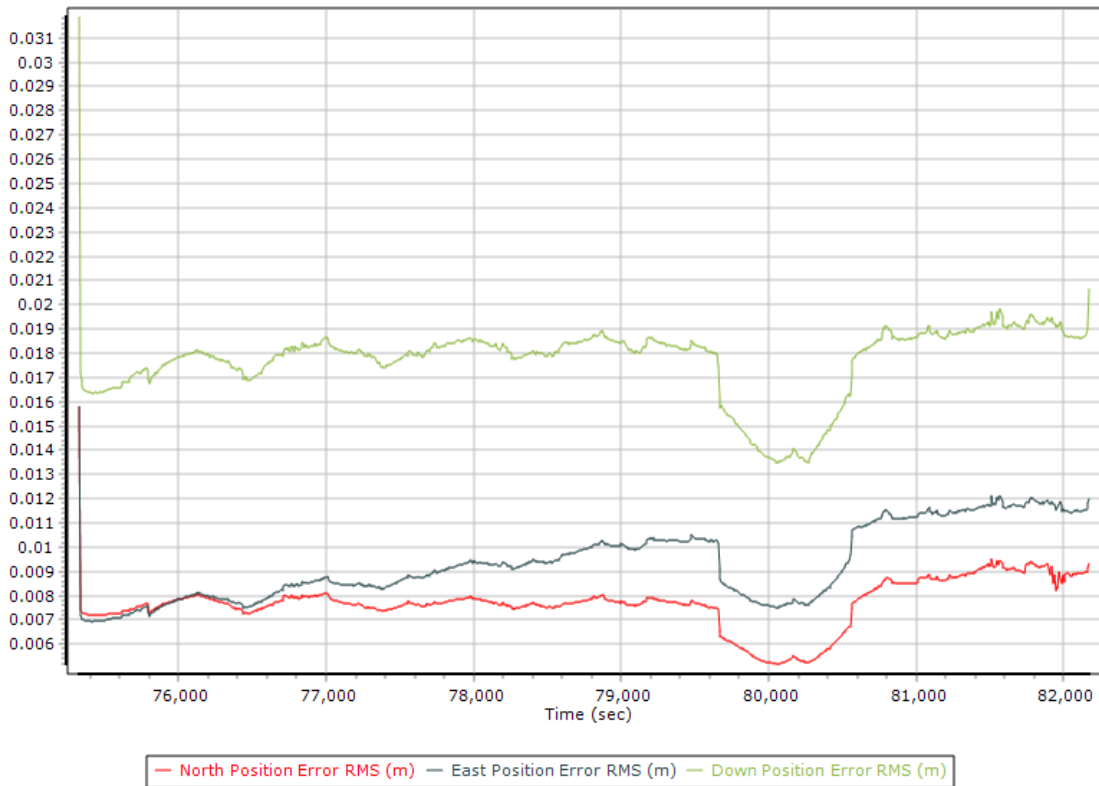
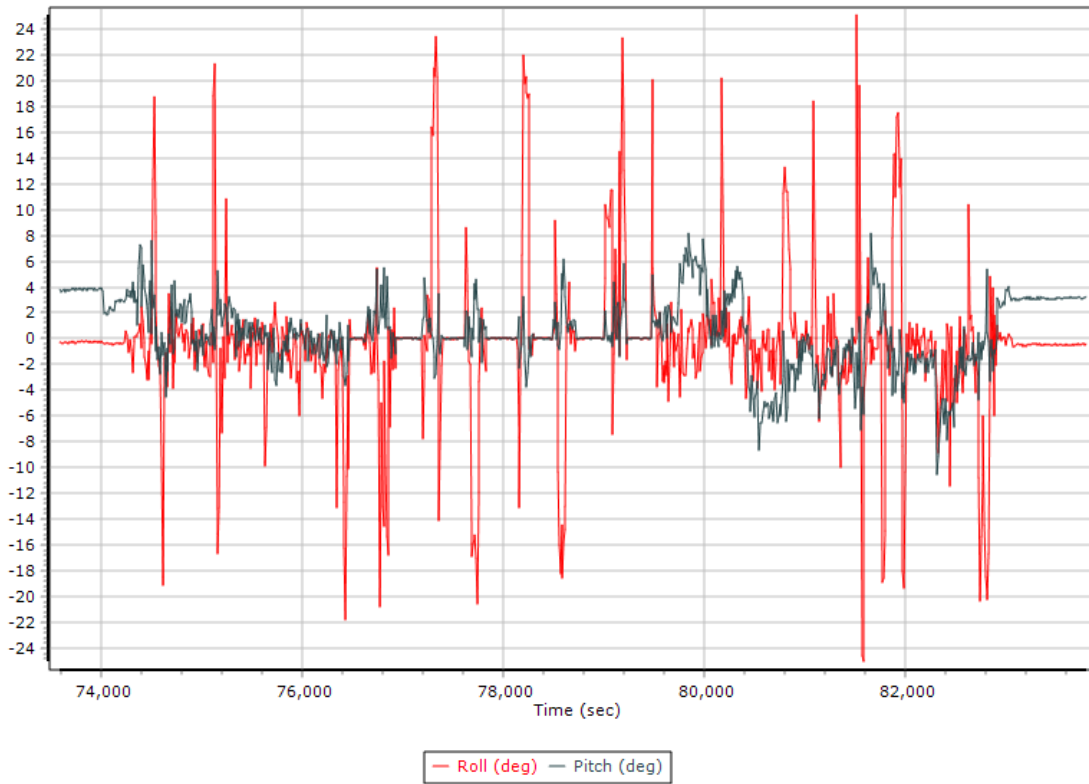
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

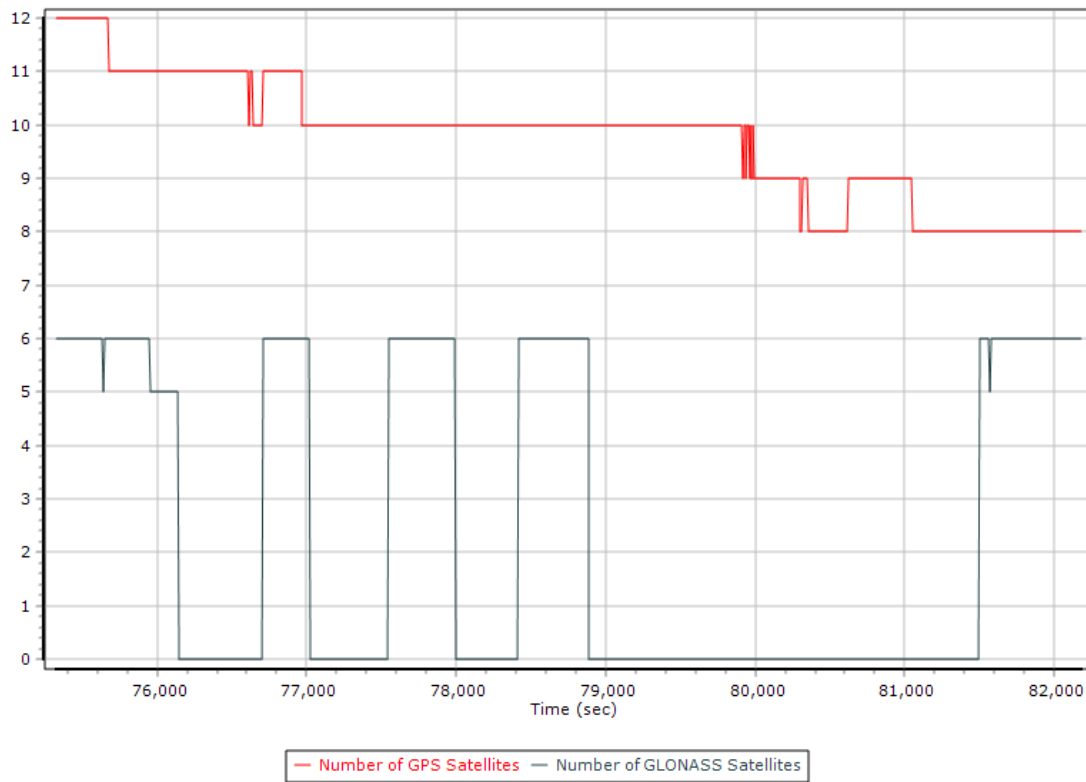
Timing

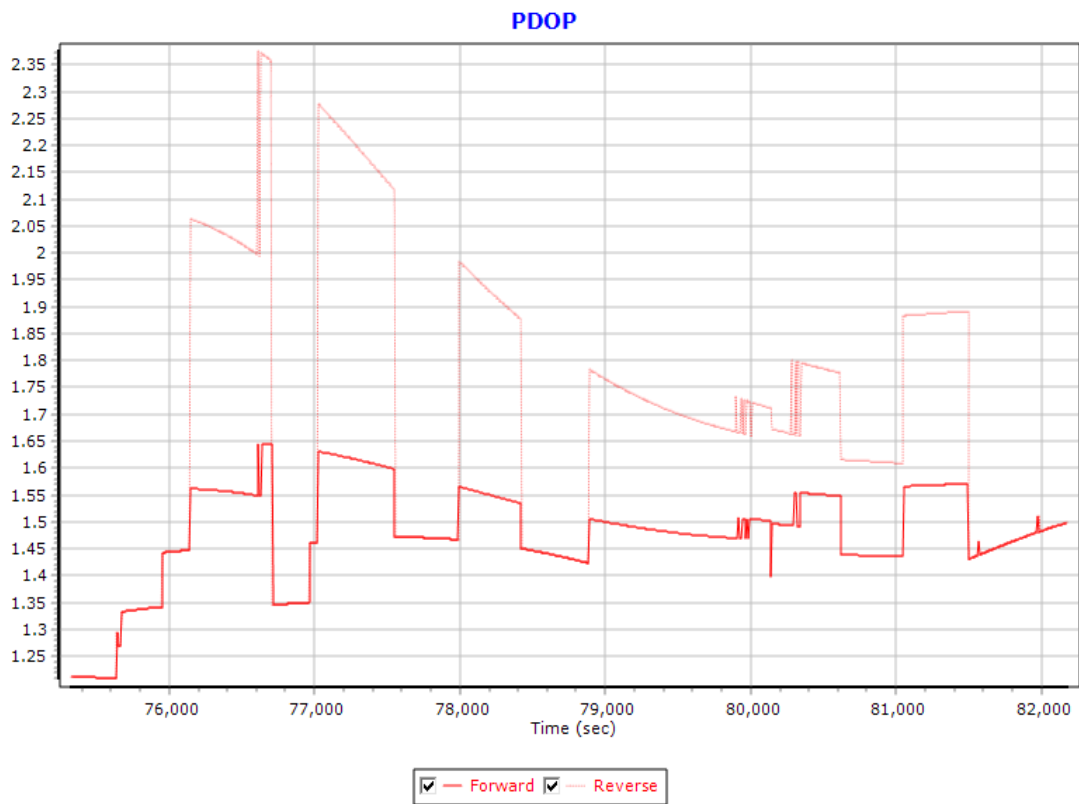
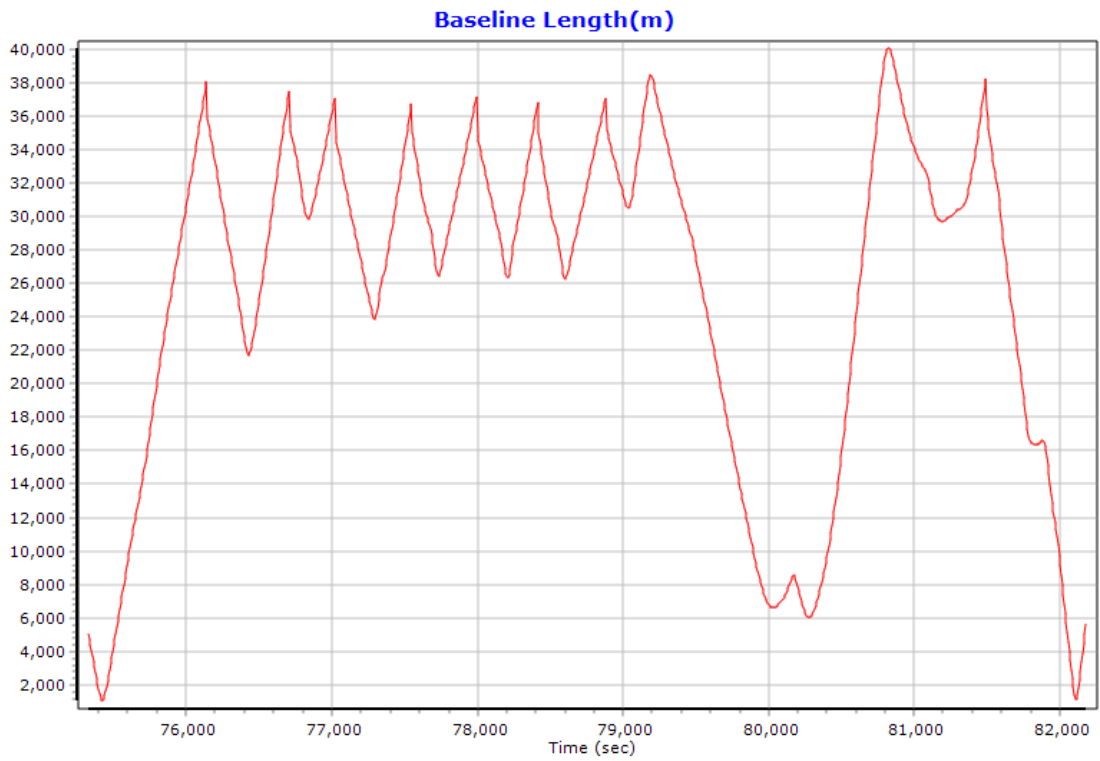
Start	75323.883	Data	Incr. (sec)
End	82180.485	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset: 18.000

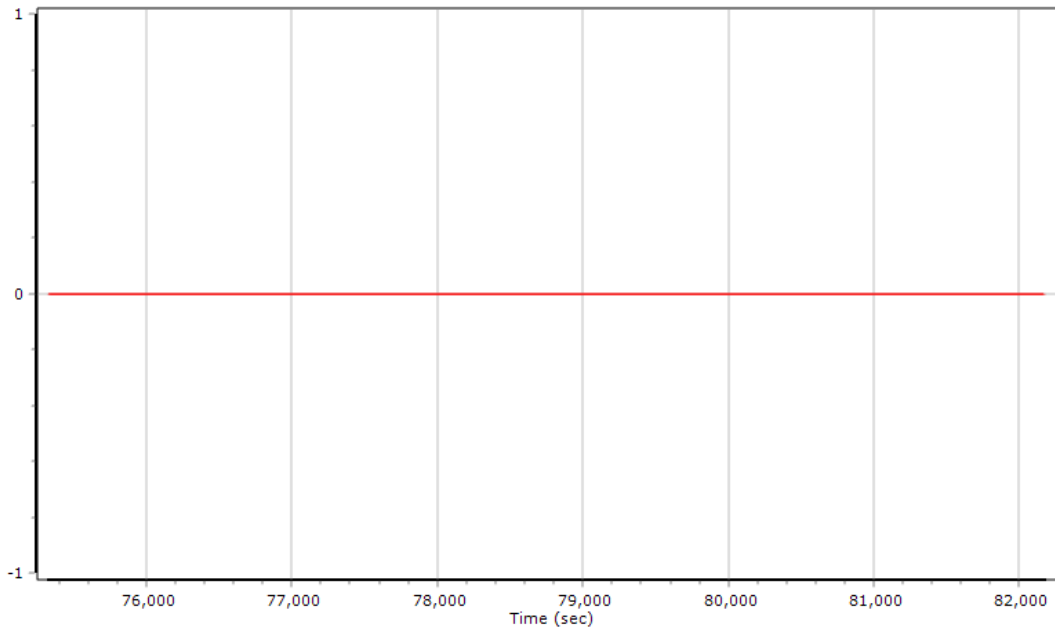








Processing mode



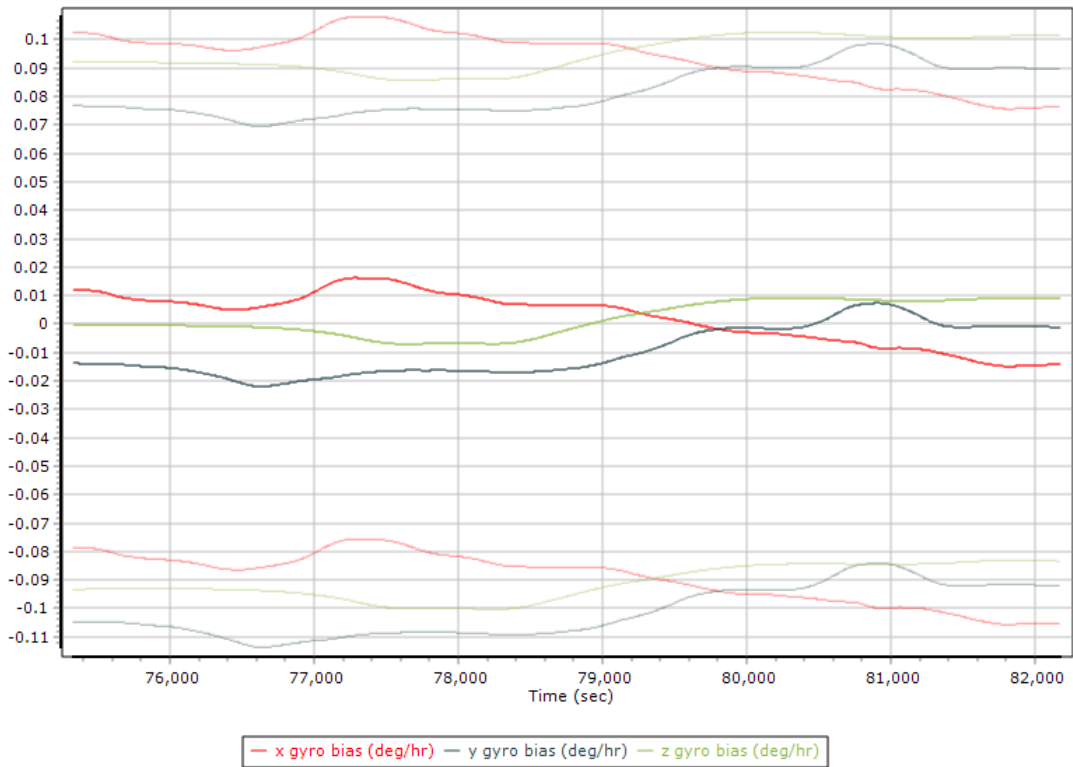
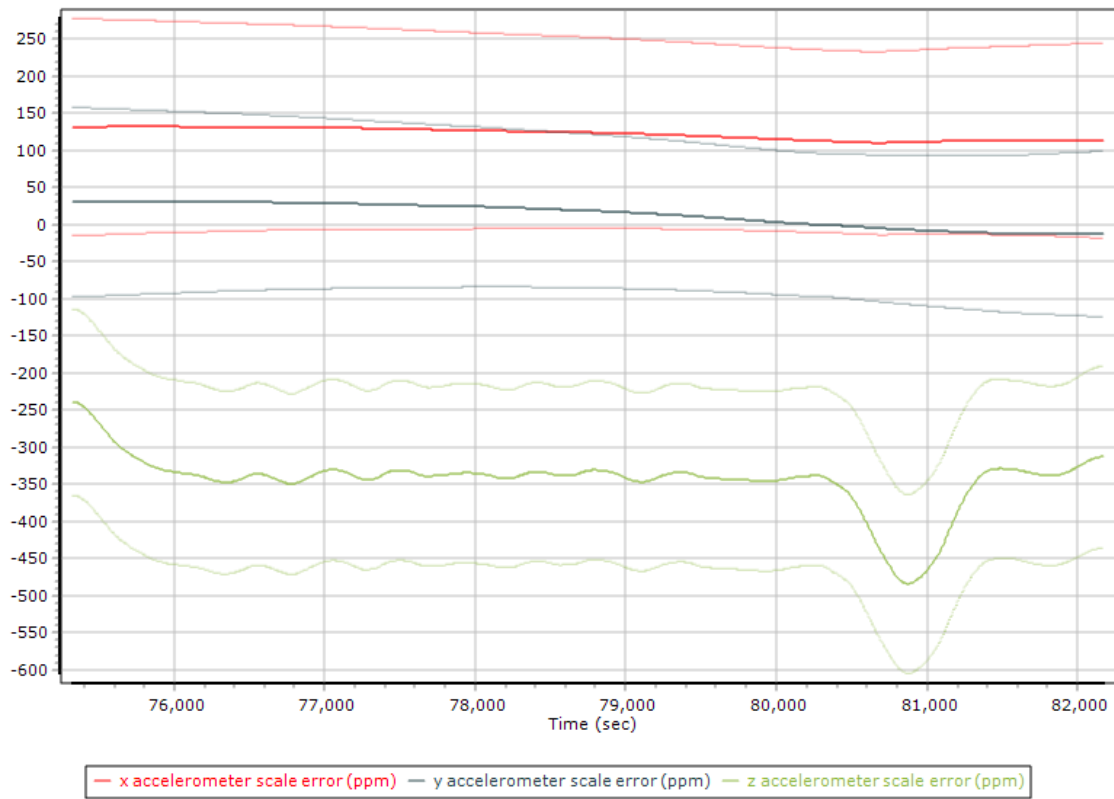
Forward Reverse

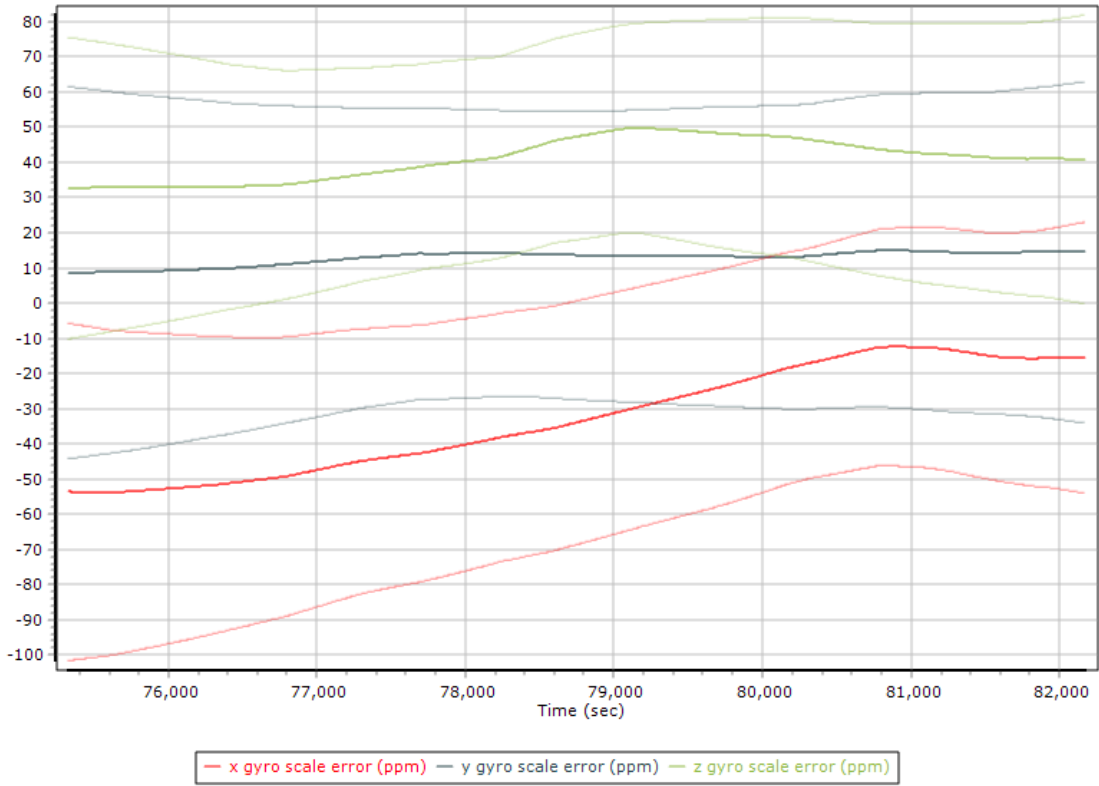
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

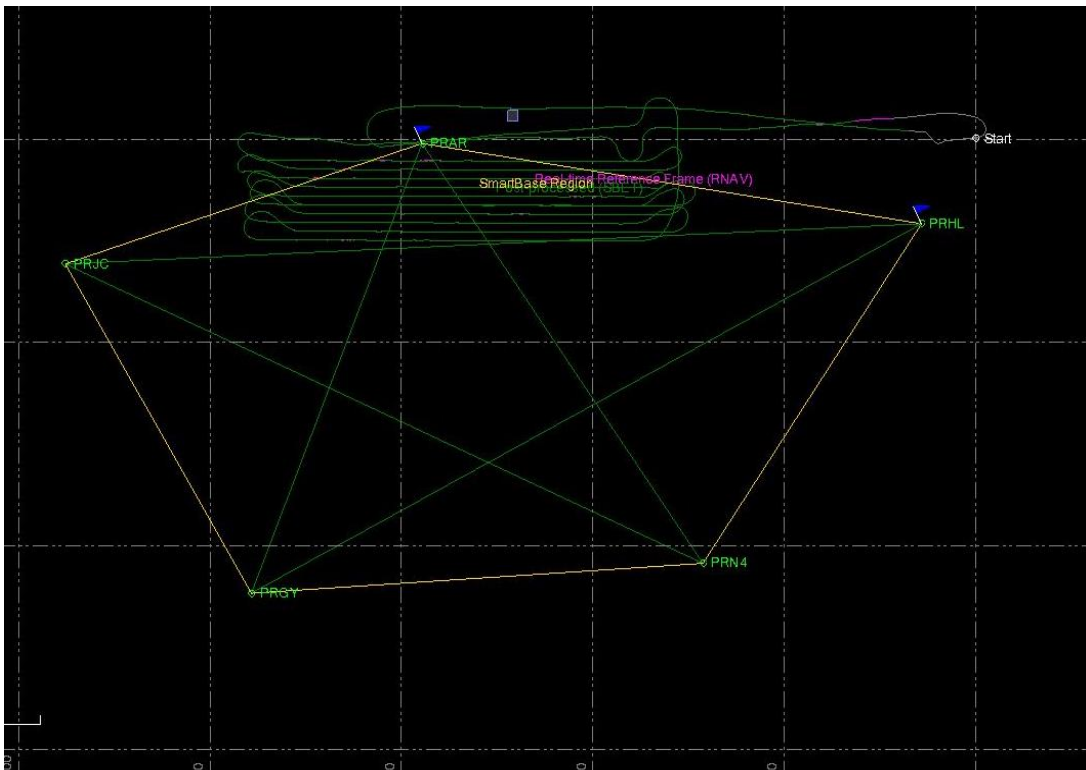


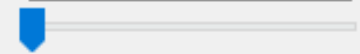
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)





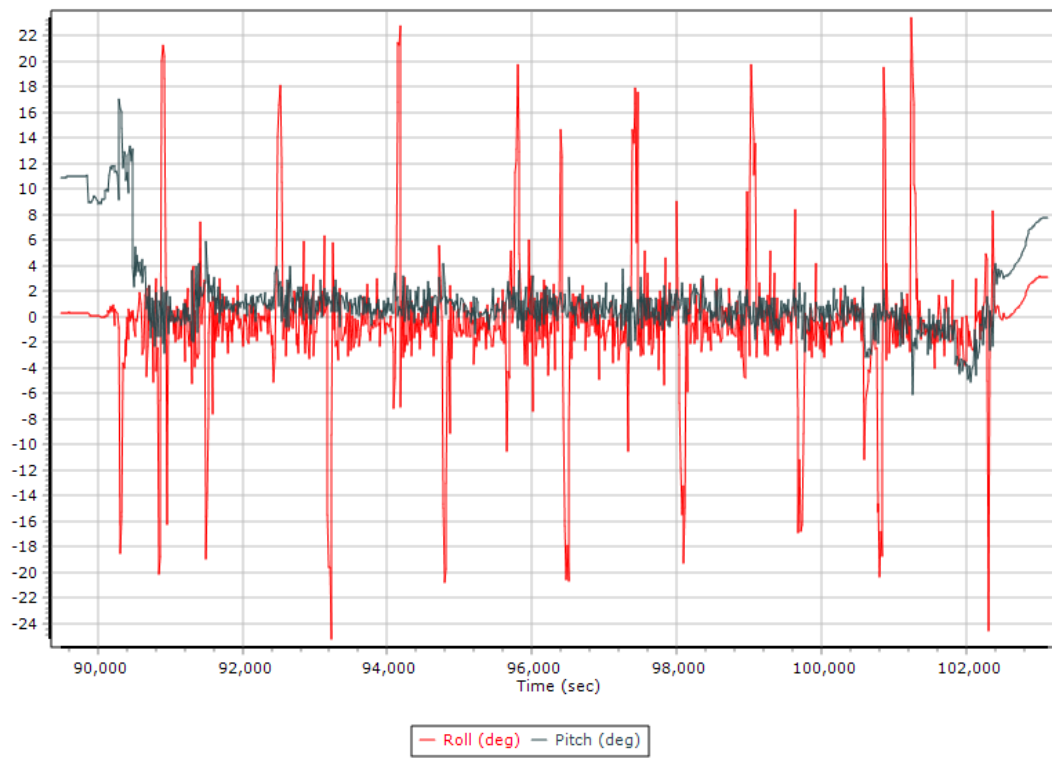
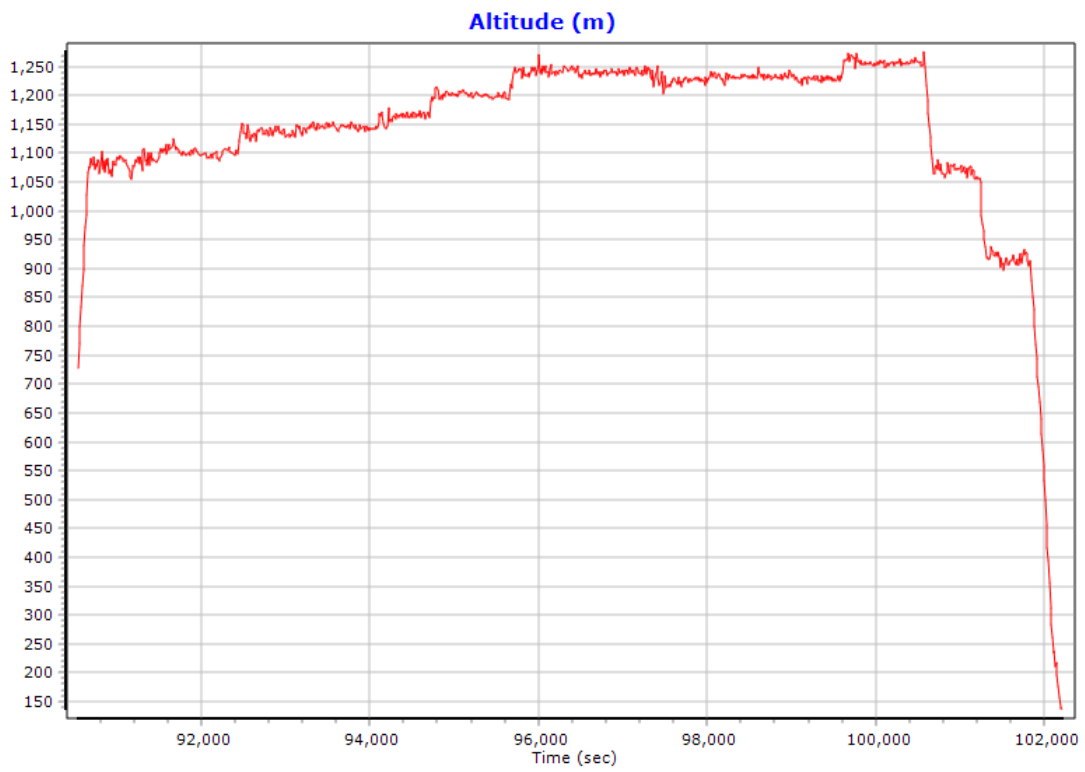
AZT18126D

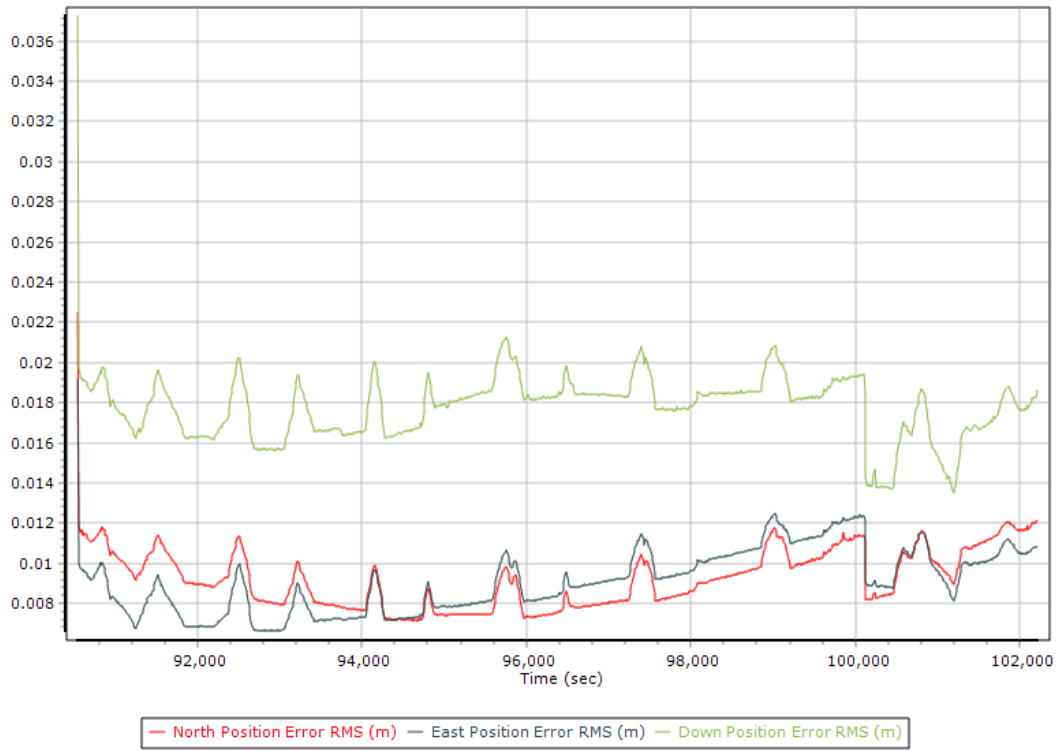


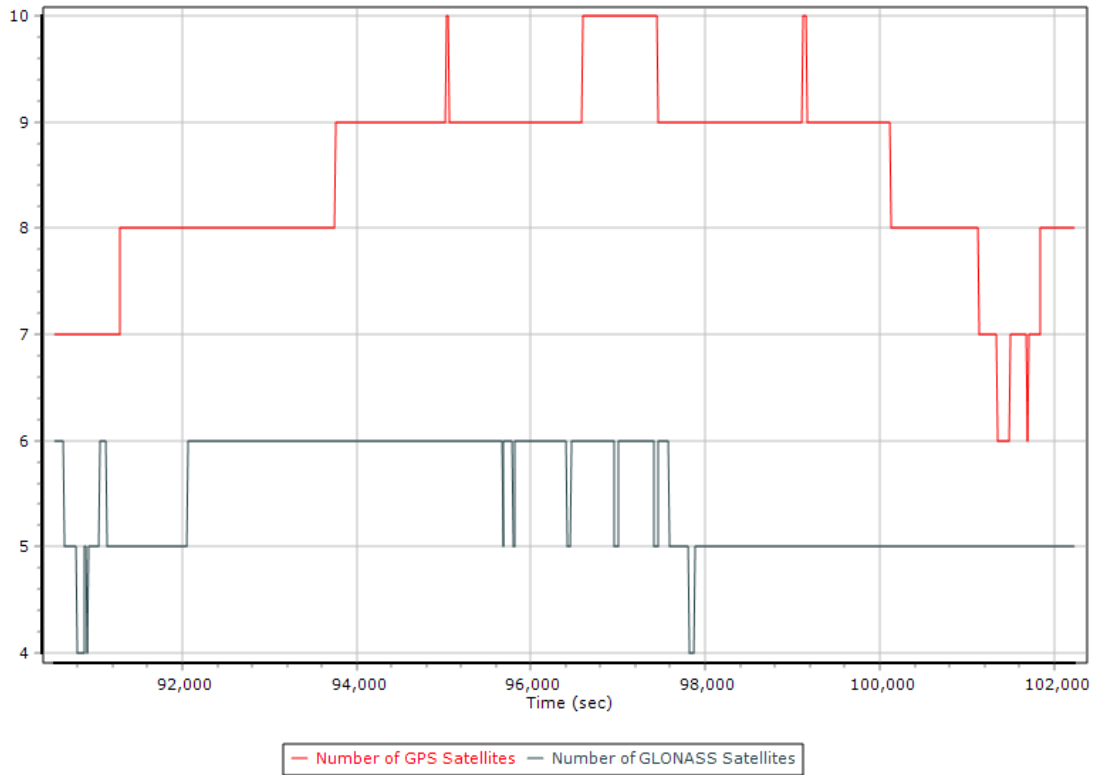
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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			
	<3cm 10cm 50cm 1m 10m		

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

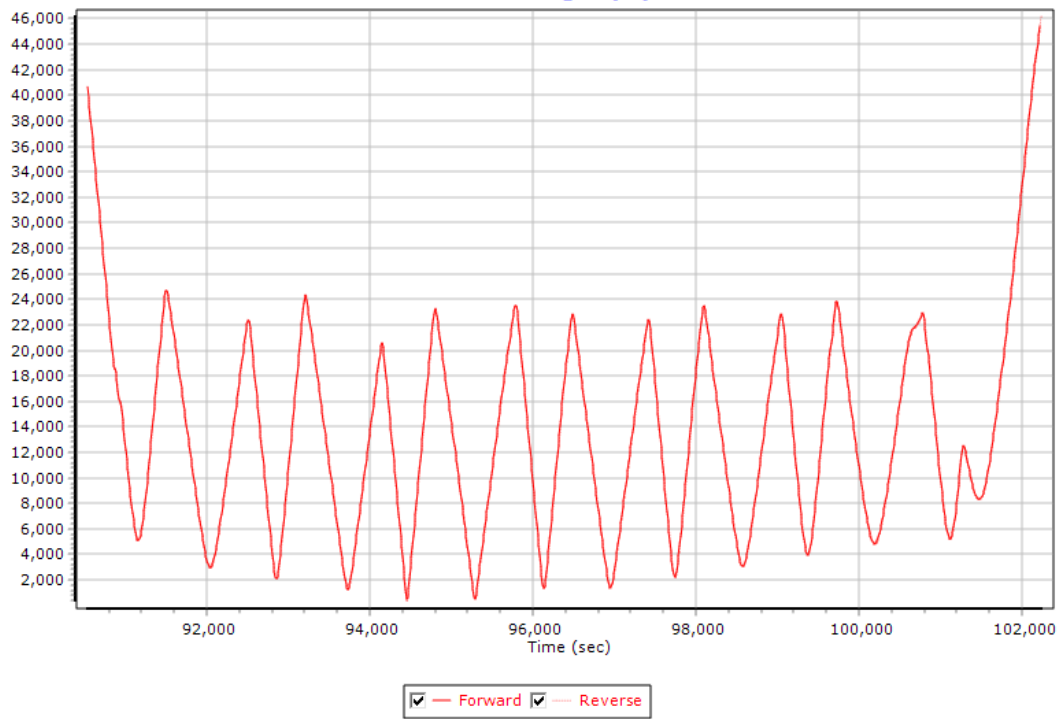
Timing			
Start	<input type="text" value="90481.679"/>	Data	Incr. (sec)
End	<input type="text" value="102236.410"/>	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000
UTC Offset	<input type="text" value="18.000"/>		



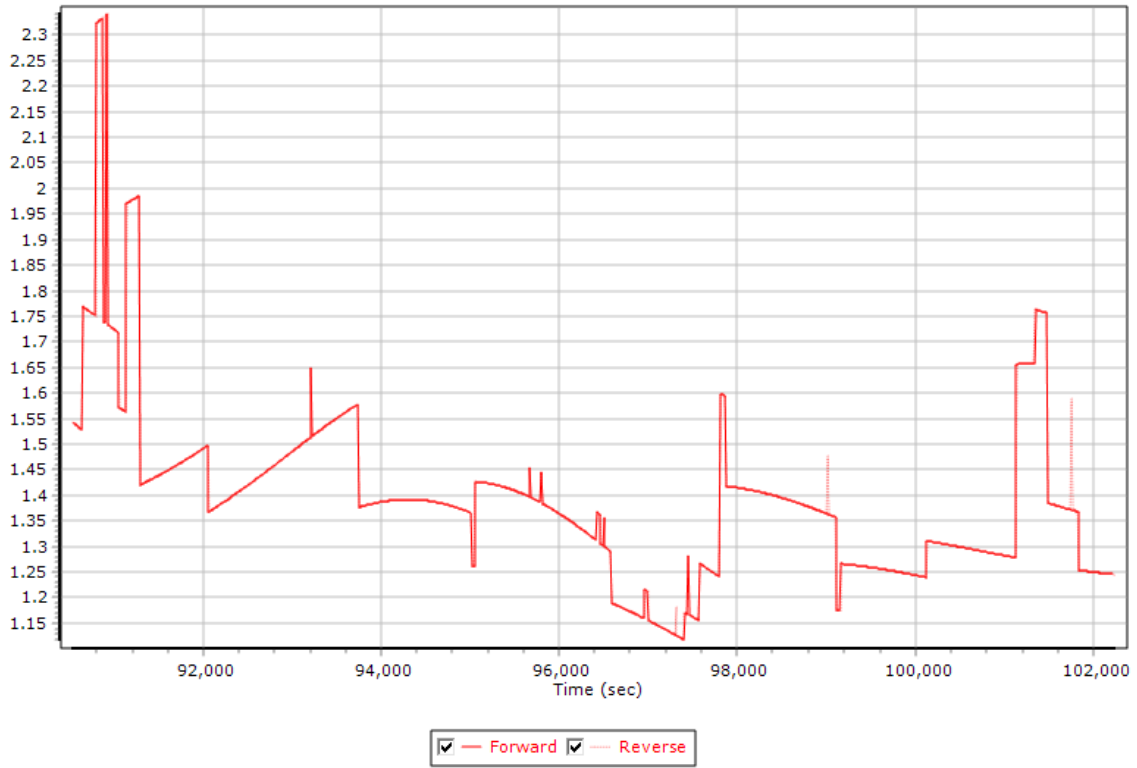




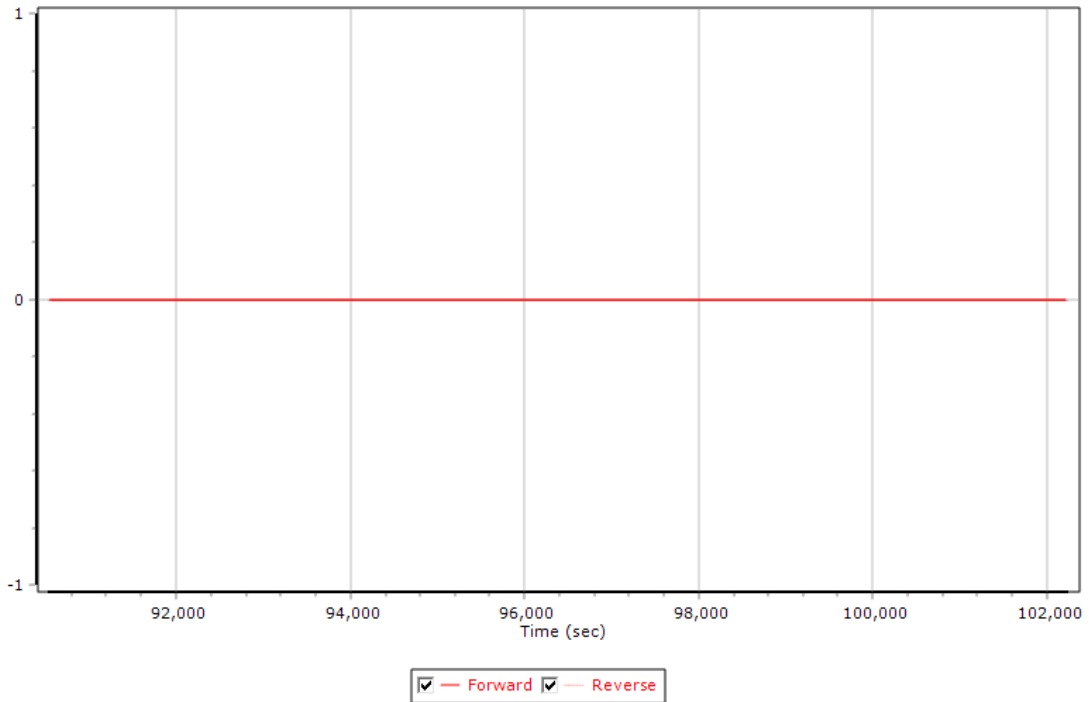
Baseline Length (m)



PDOP

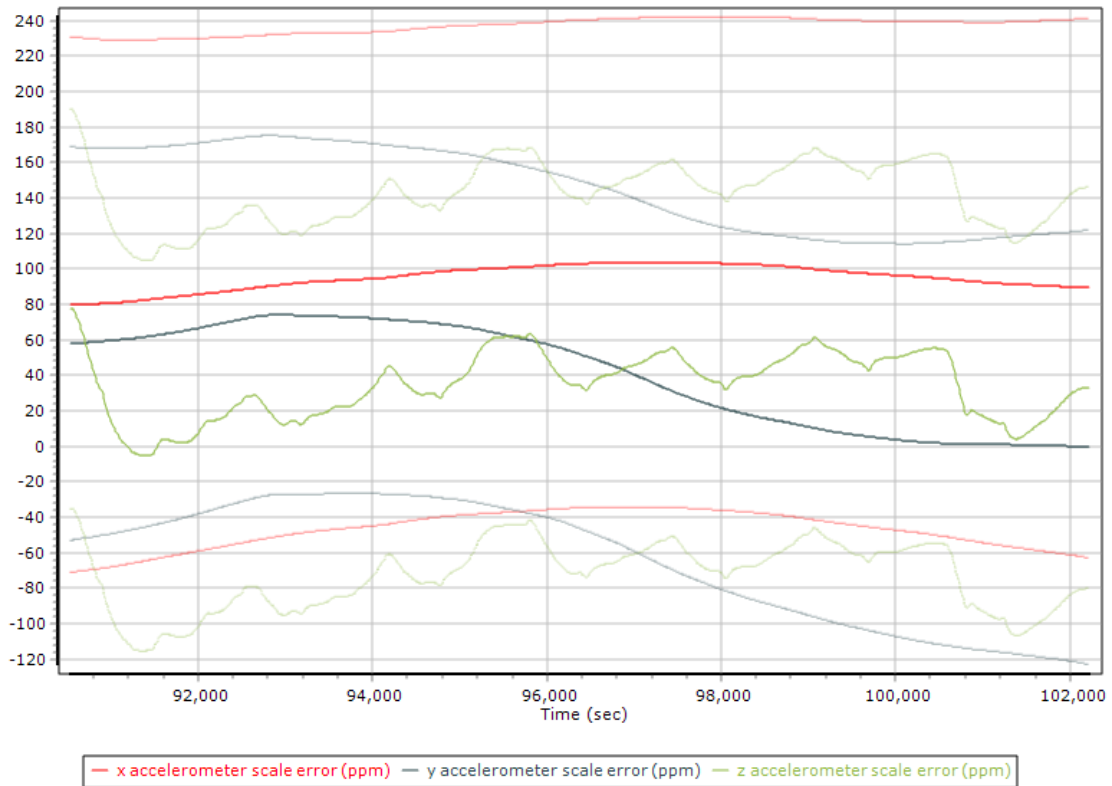
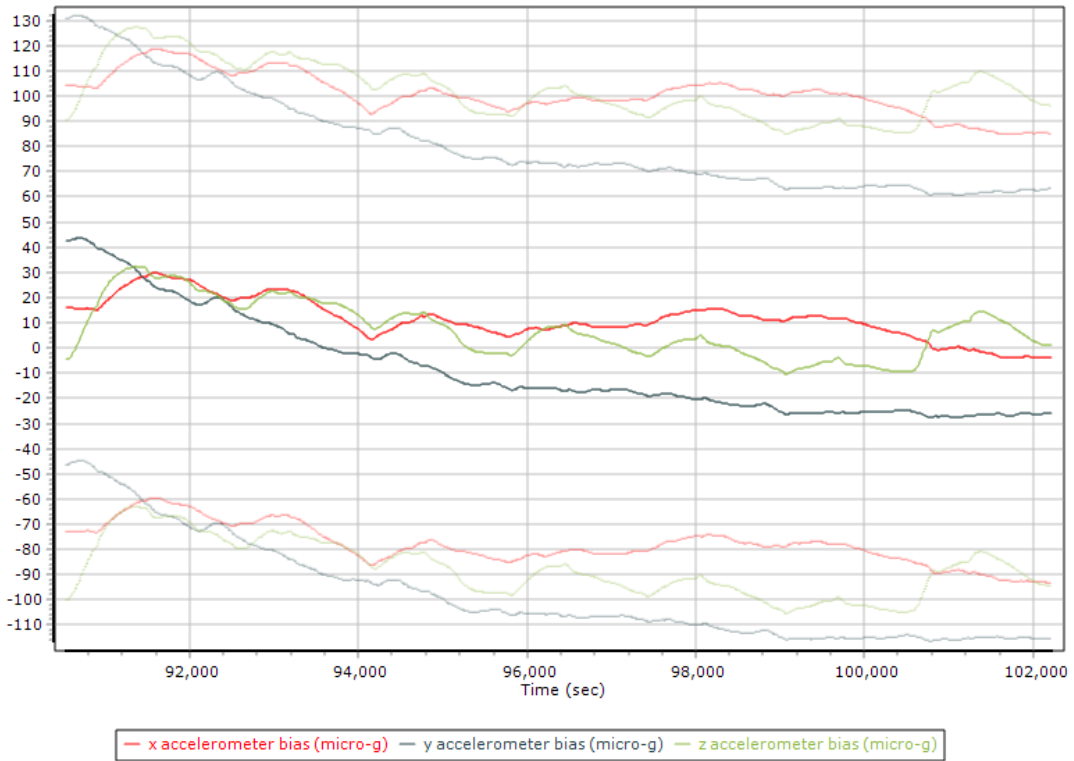


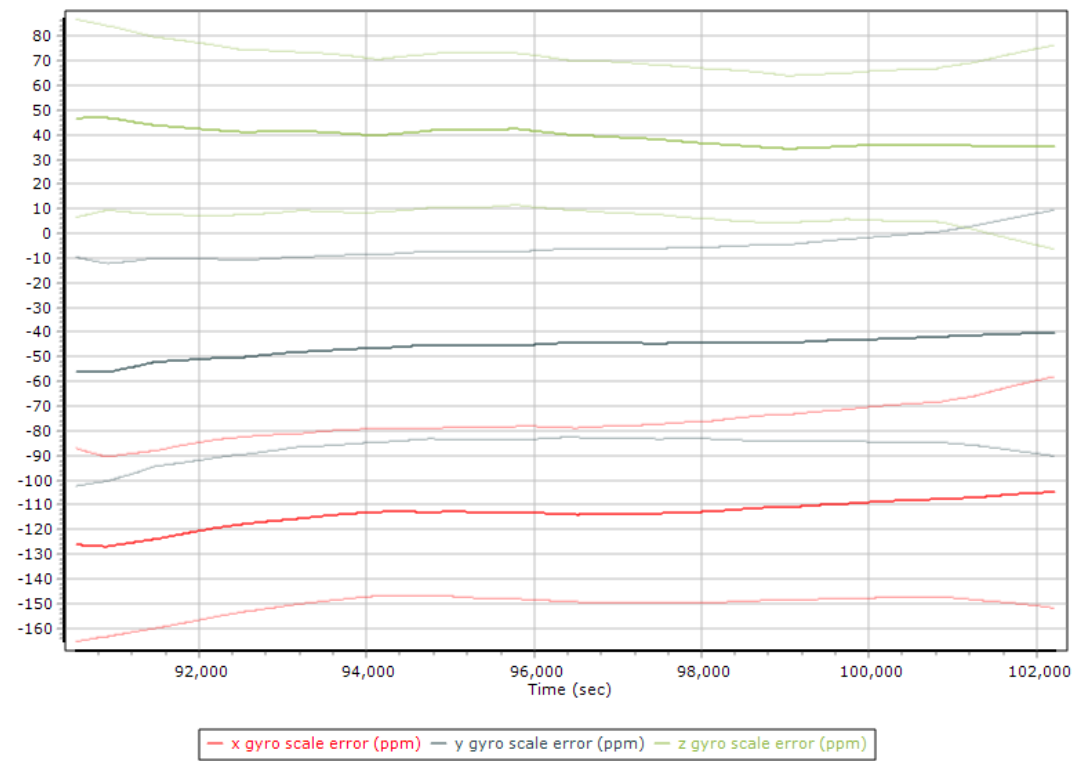
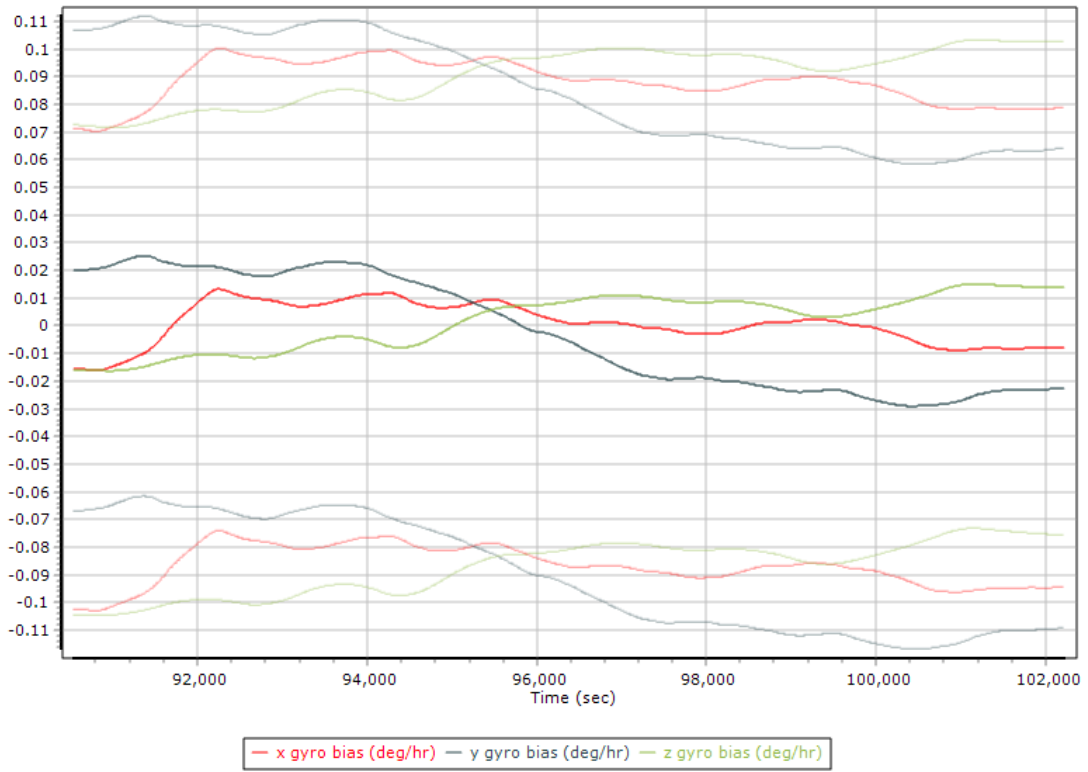
Processing mode



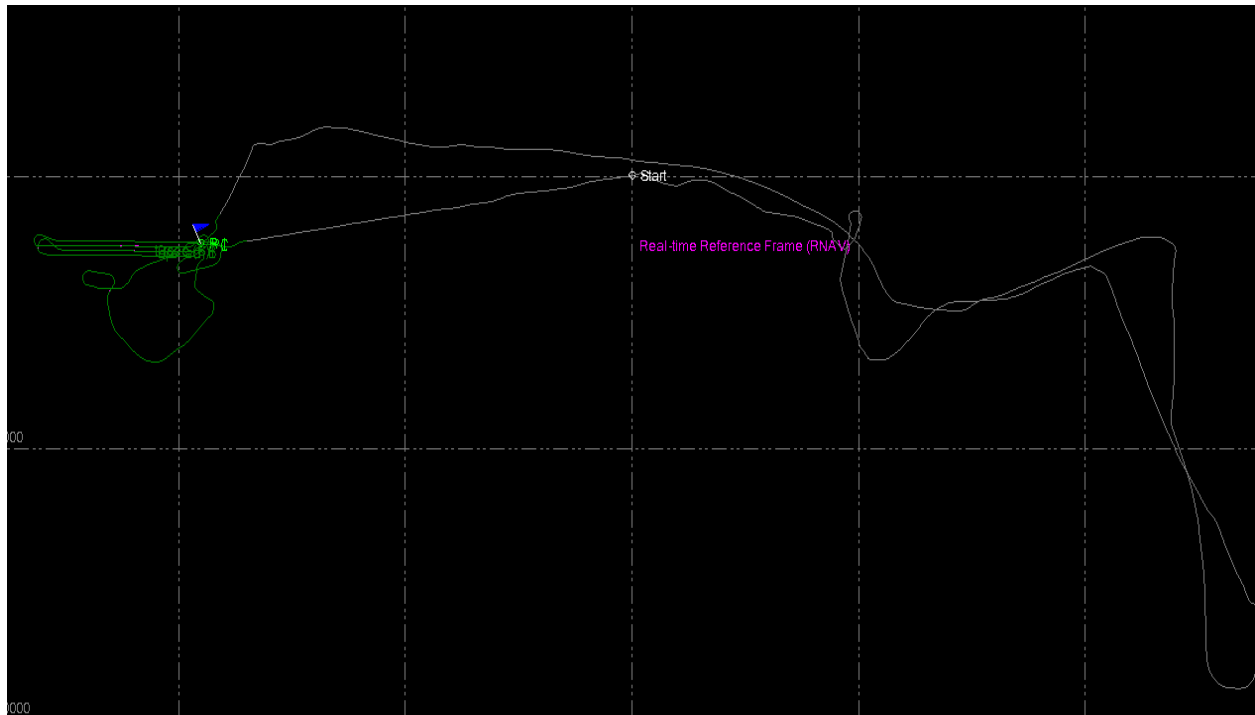
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





AZT18127A



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.

Timing

Start

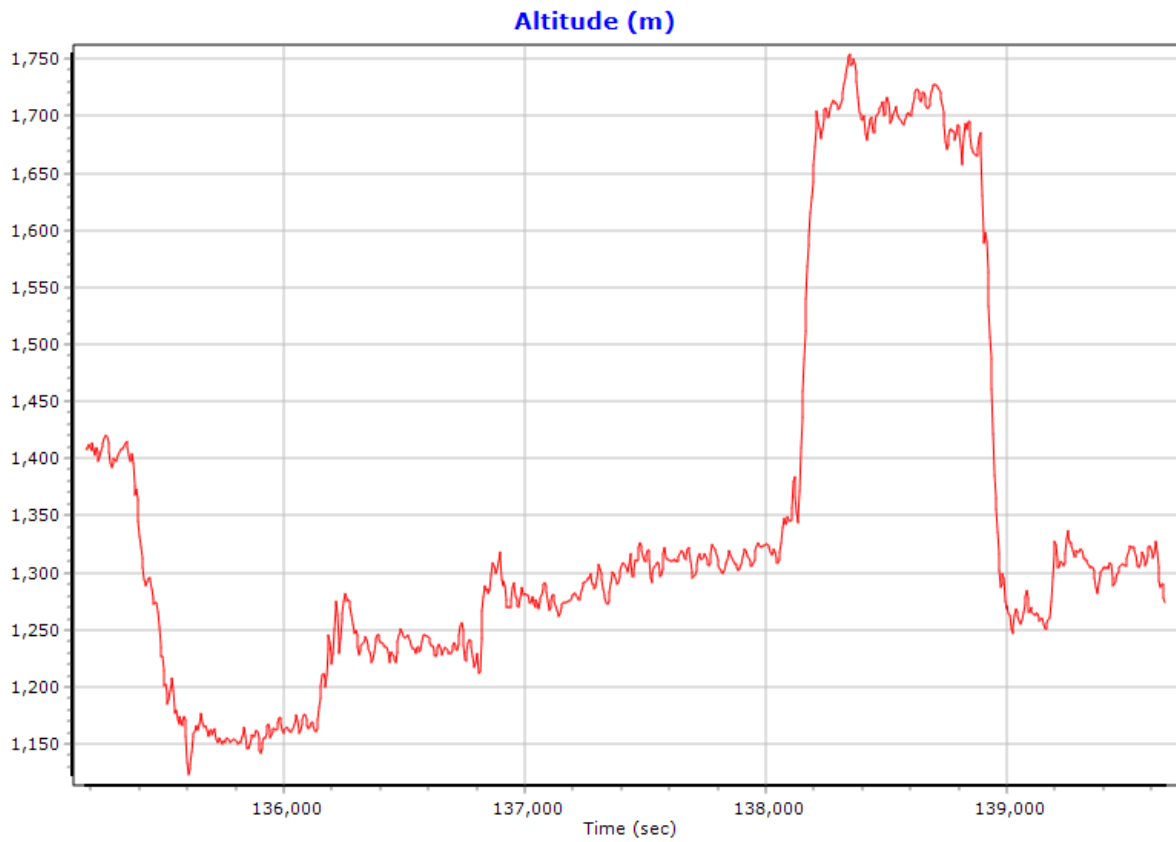
End

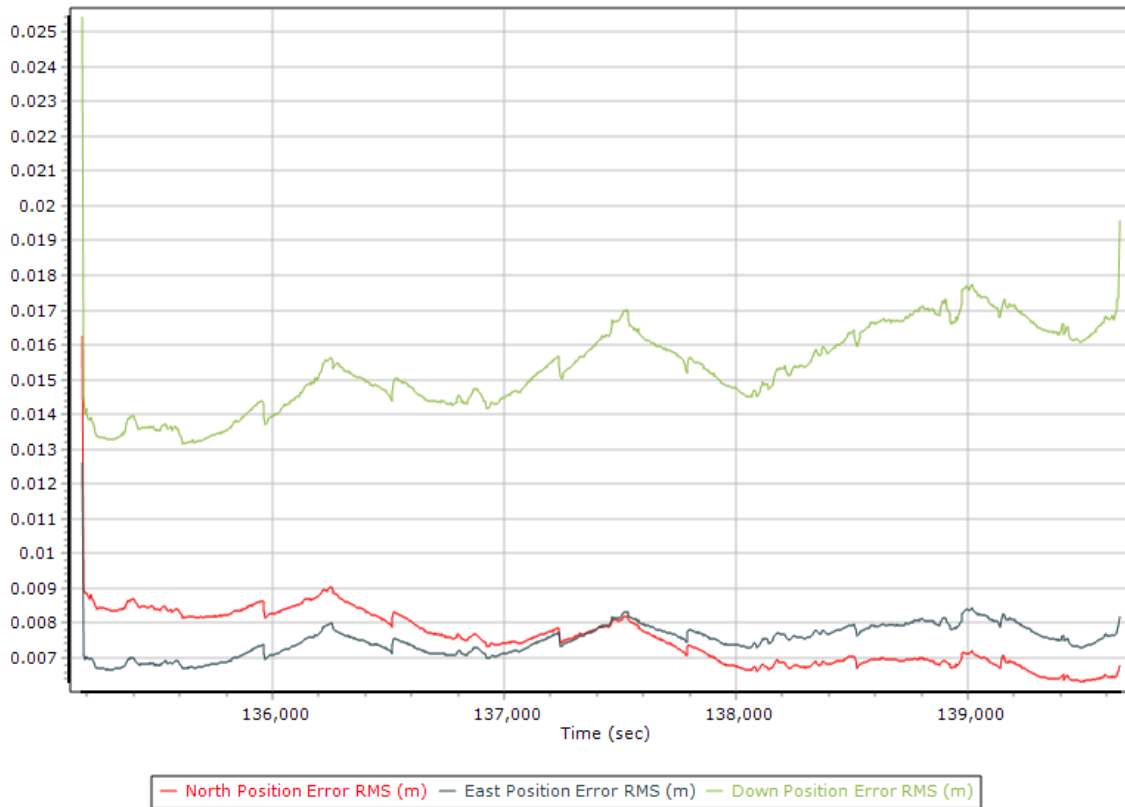
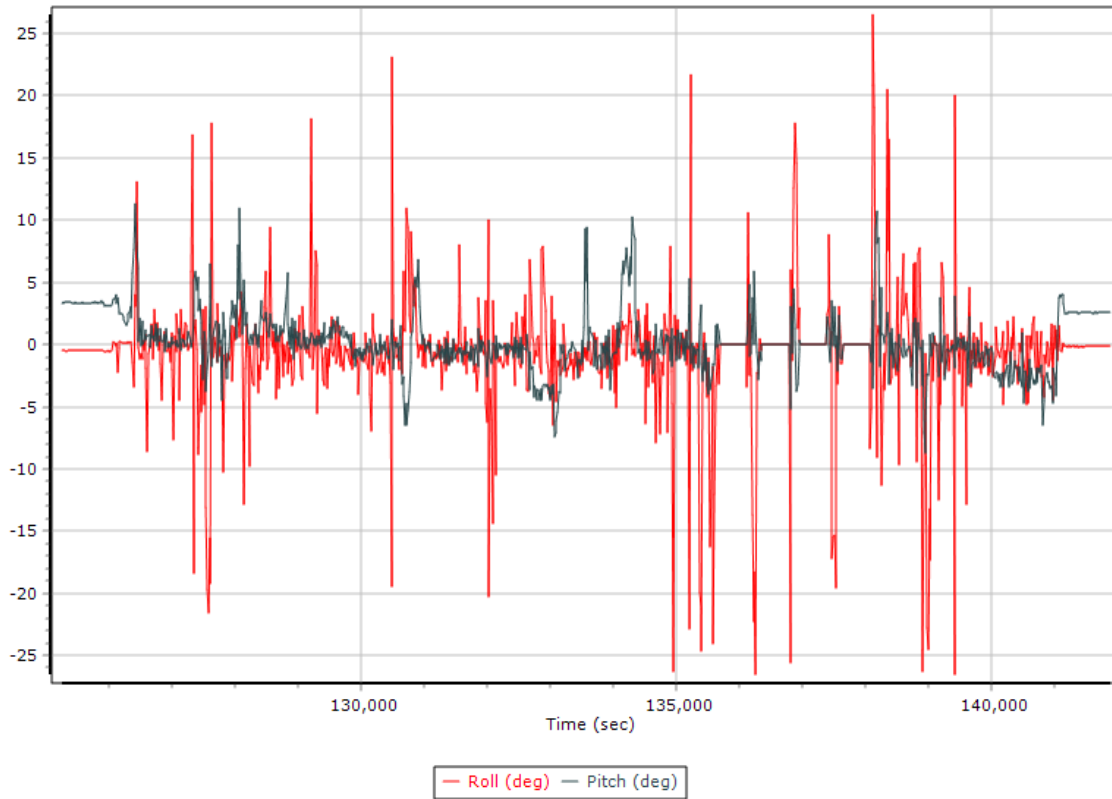
Entire time interval

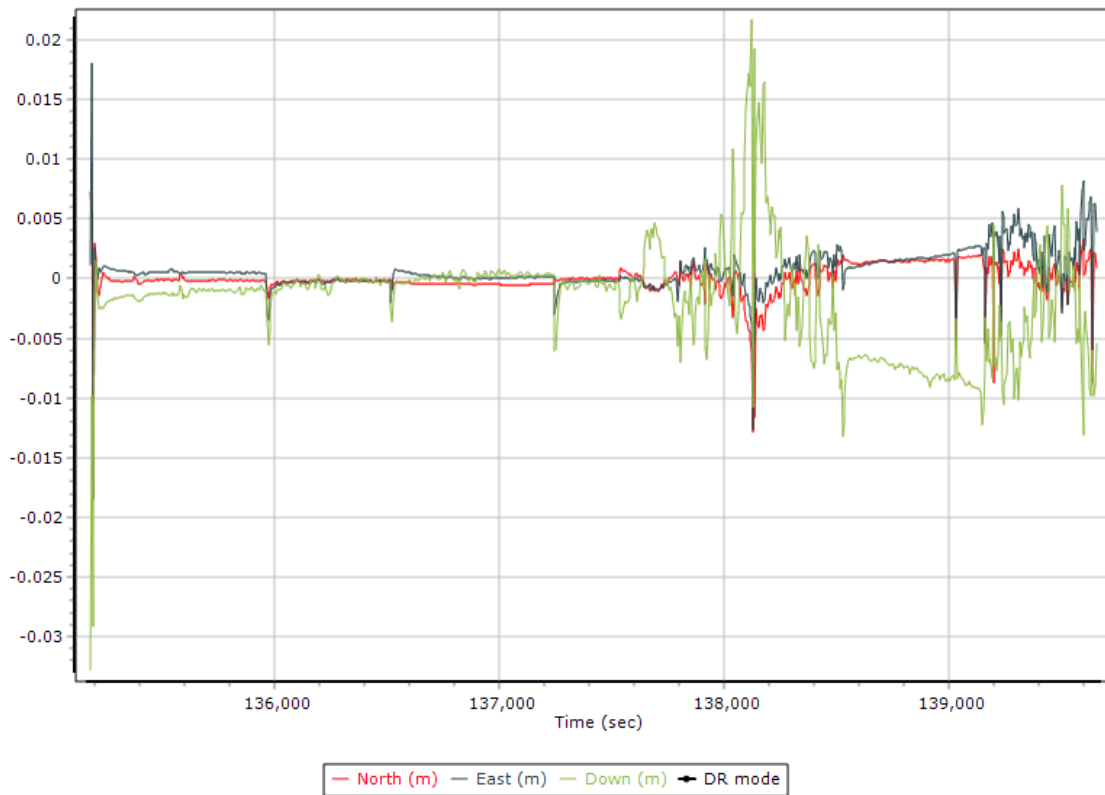
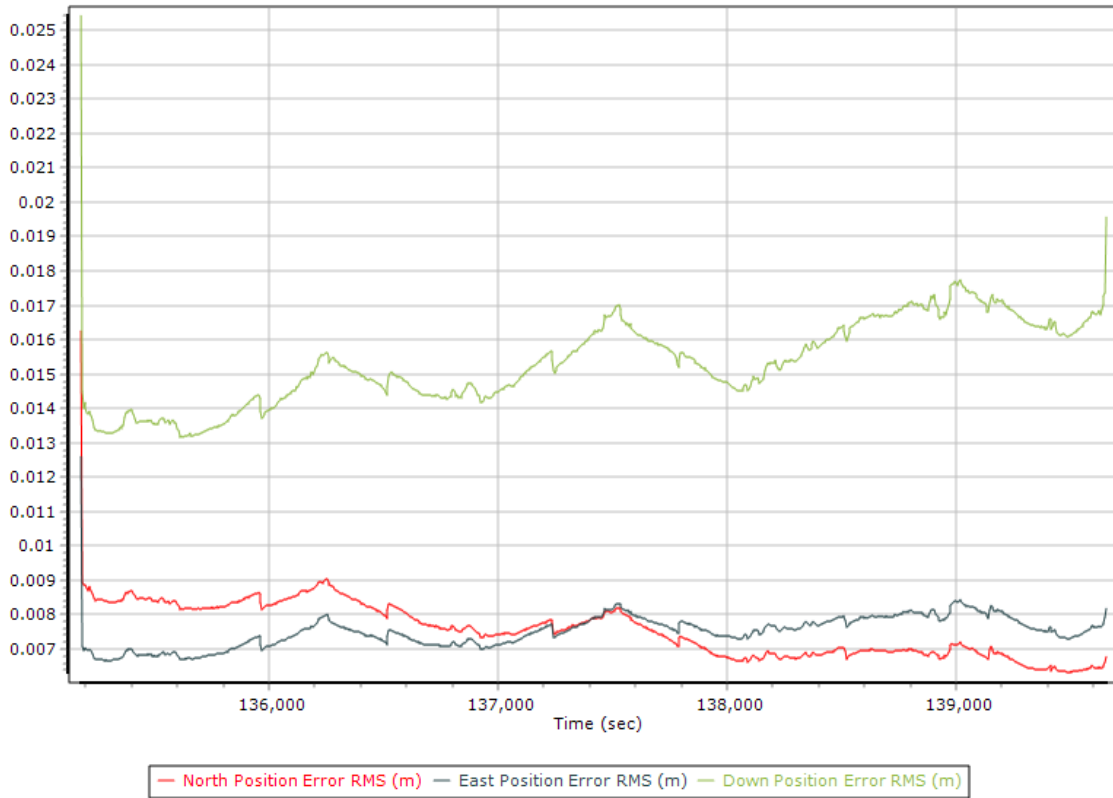
Seconds of start week

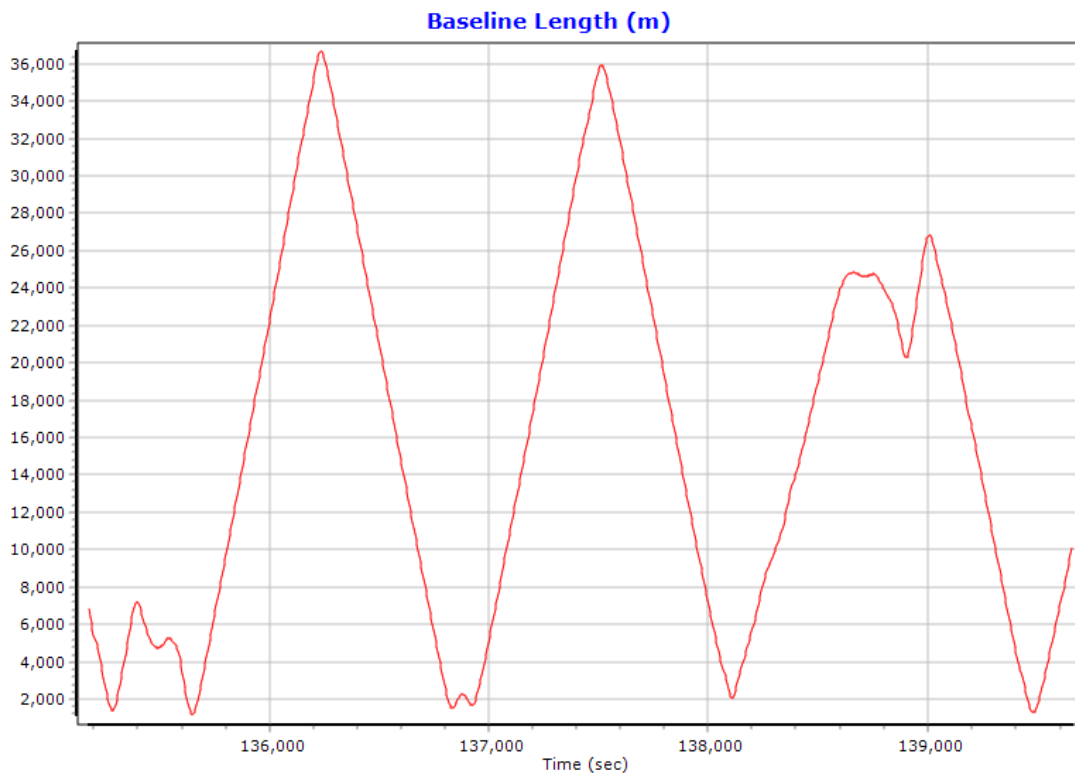
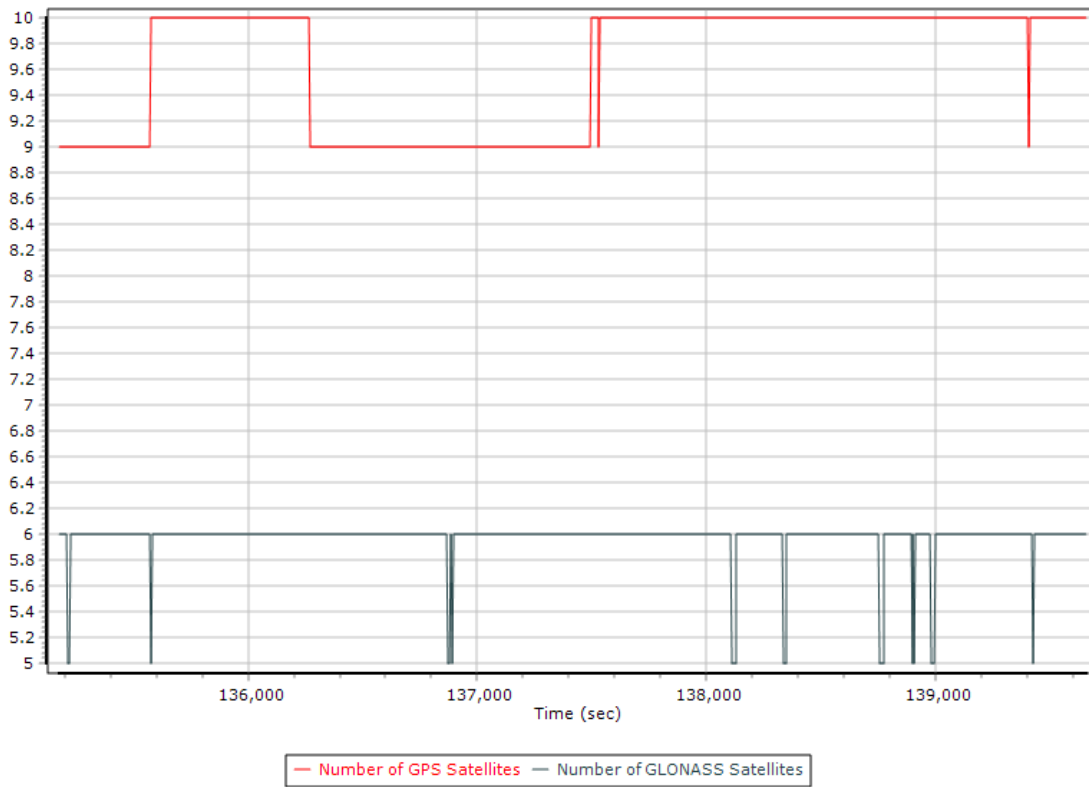
UTC Offset

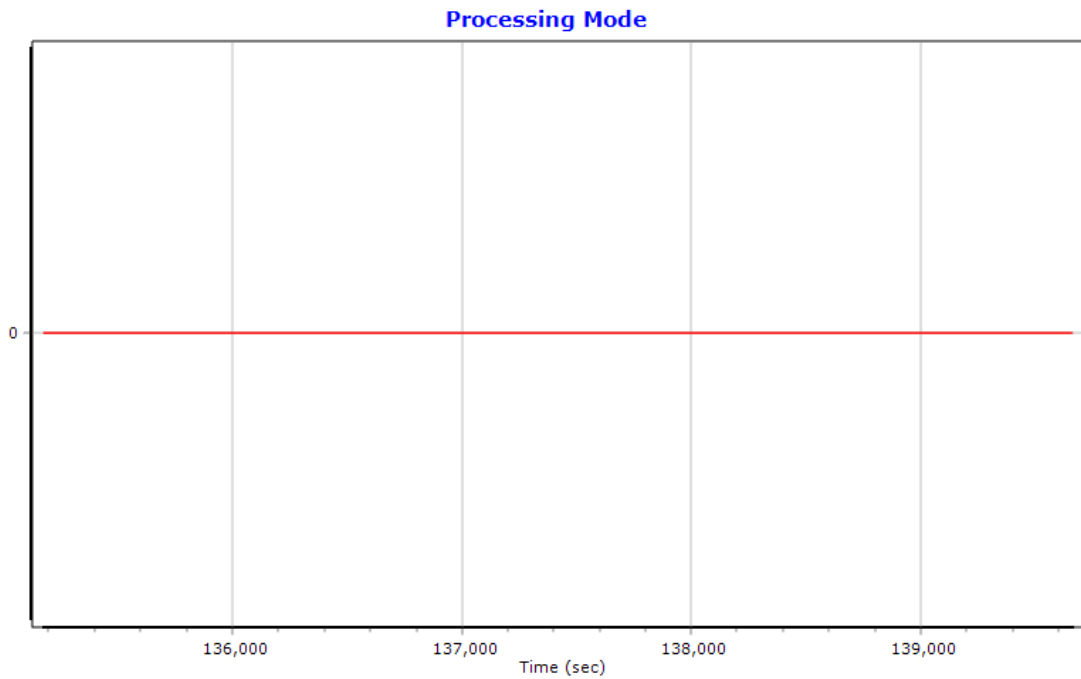
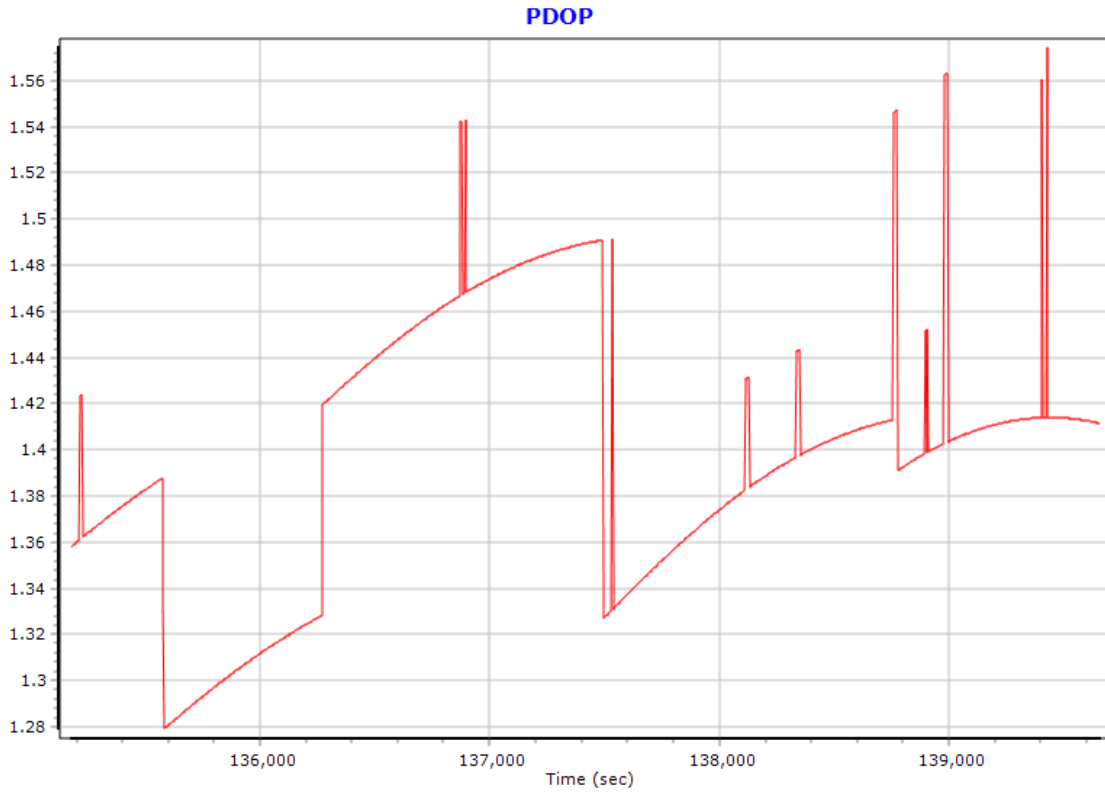
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000







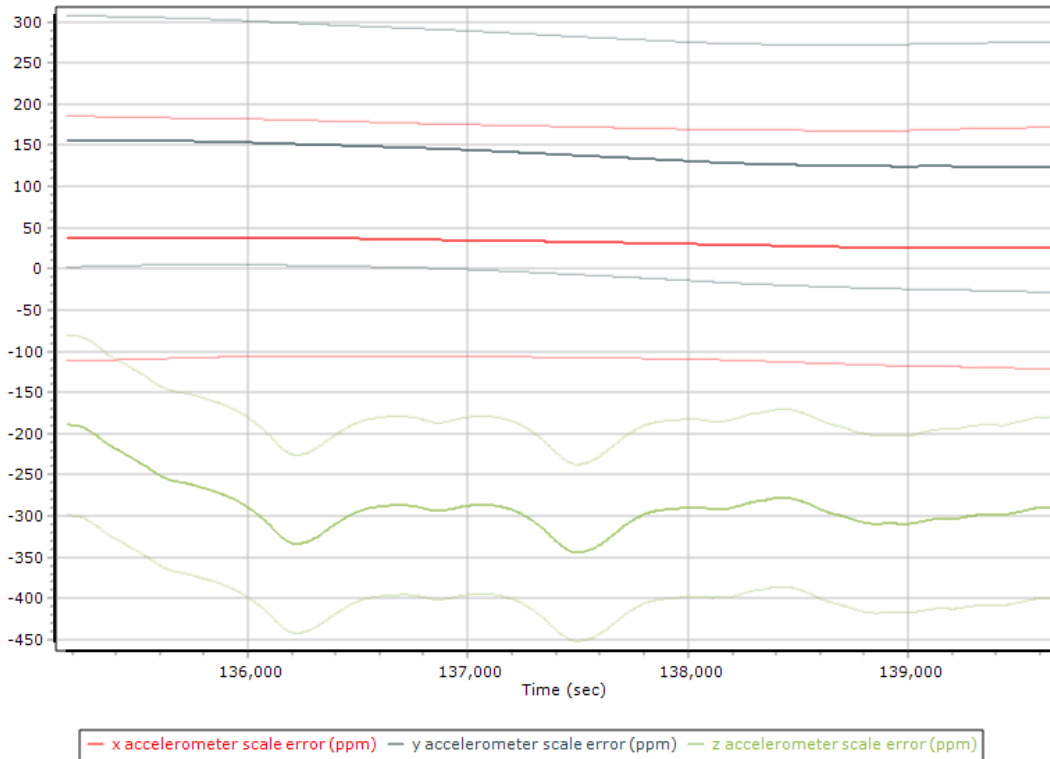
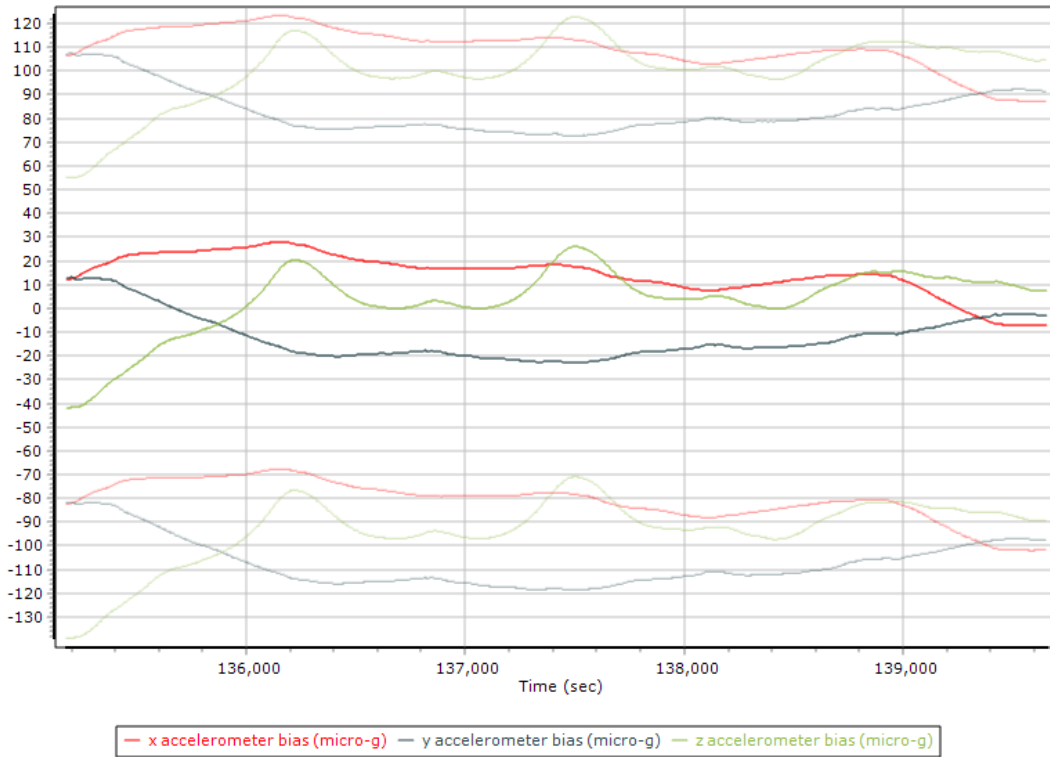


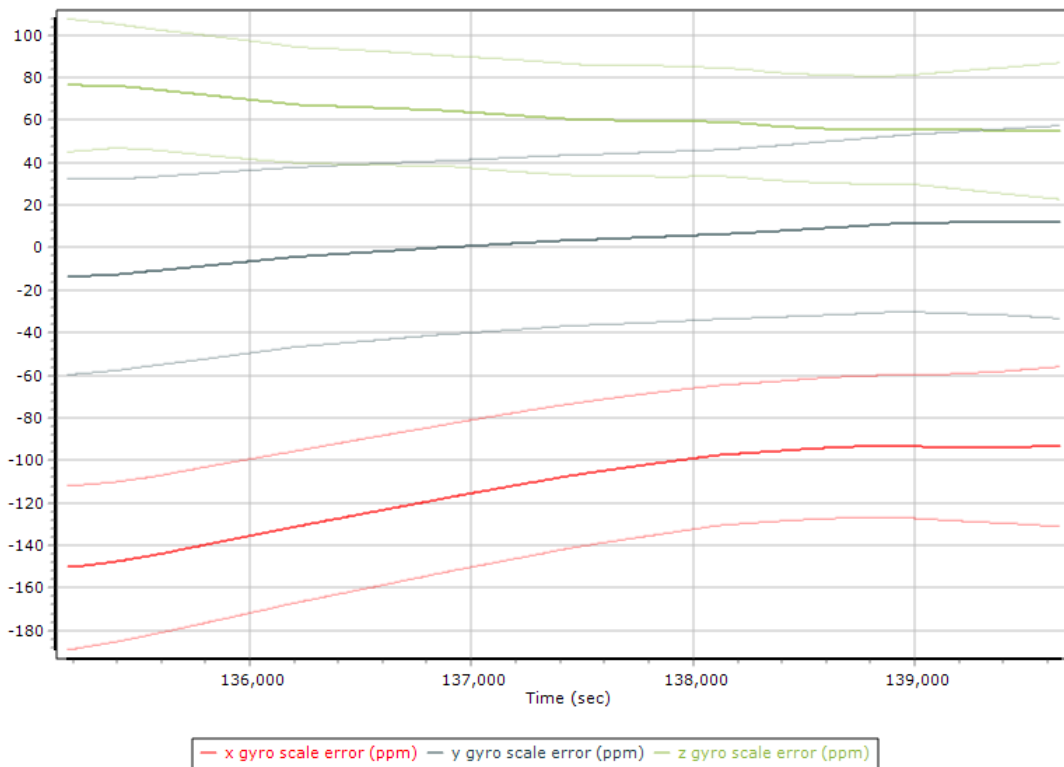
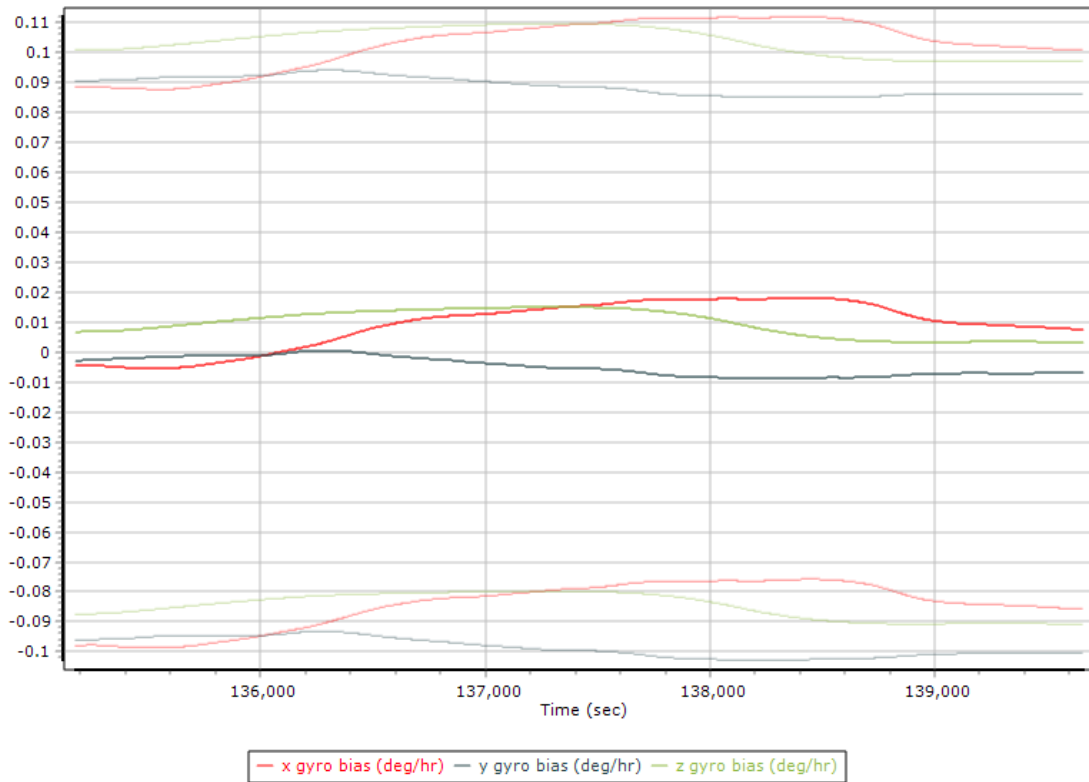


Forward Reverse

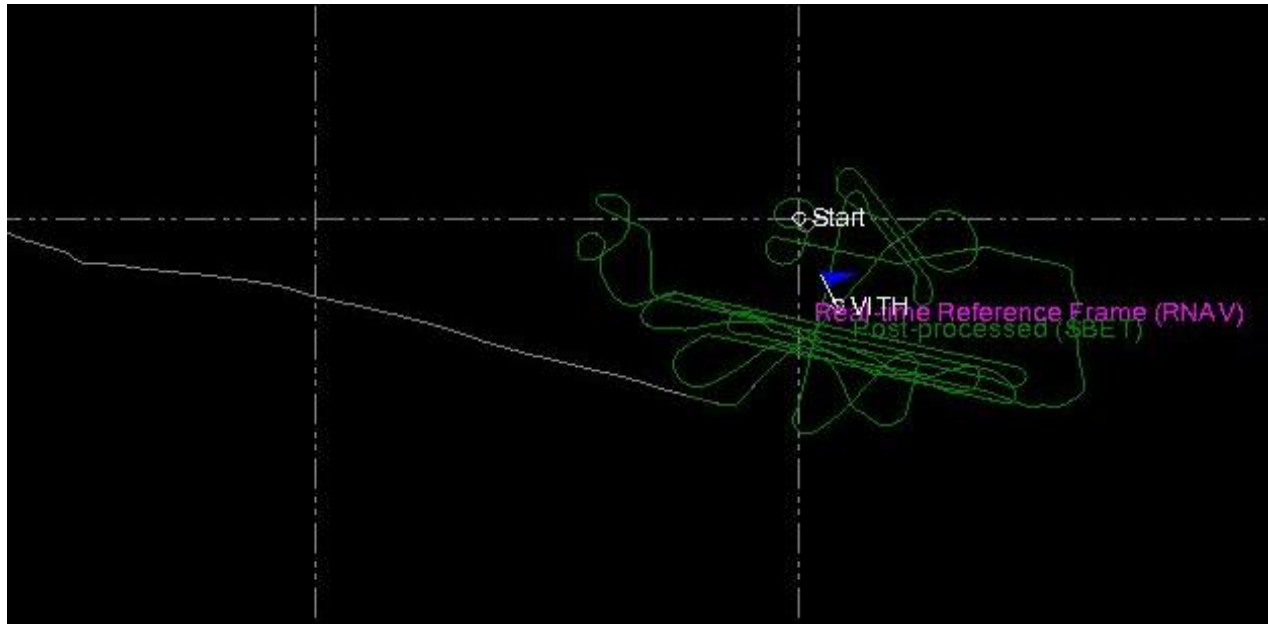
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





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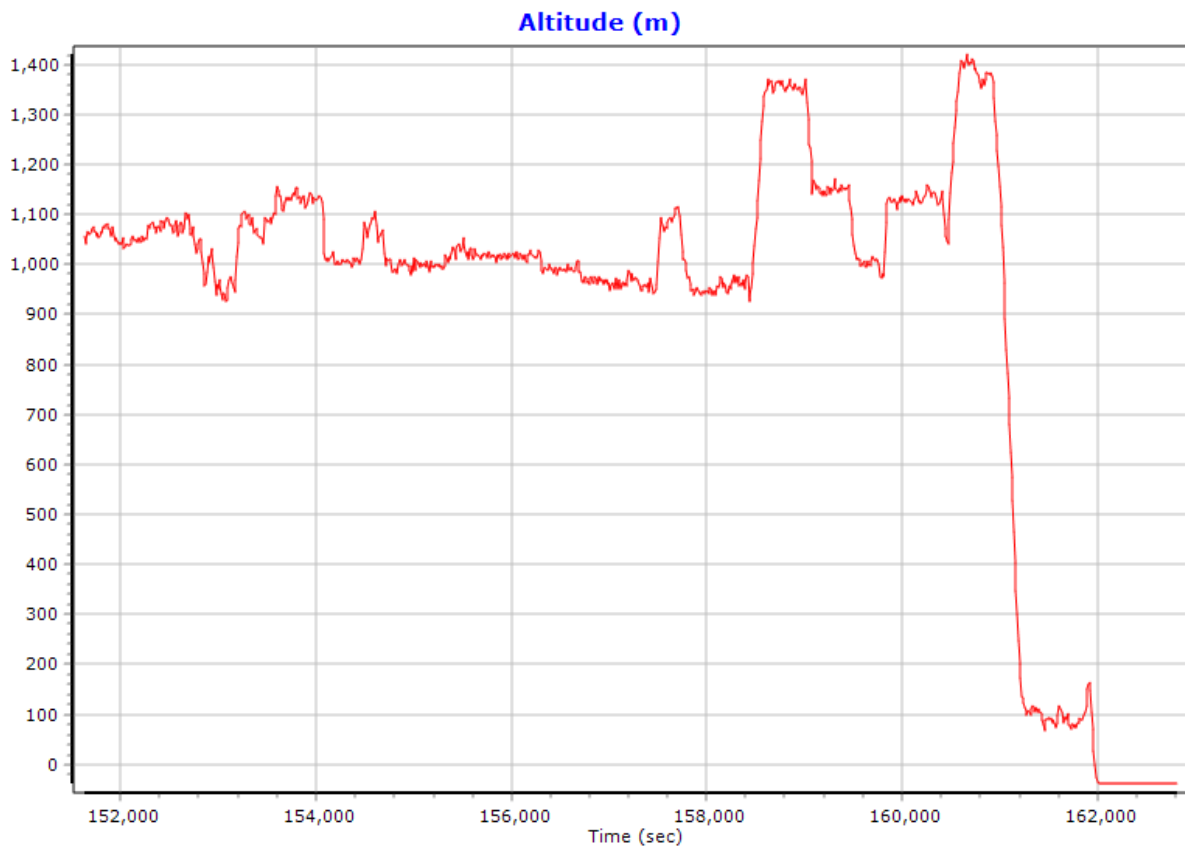
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	-0.034 m	X	0.000 deg
Y	-0.010 m	Y	0.000 deg
Z	-0.352 m	Z	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm		Aircraft to Stabilized Mount Mounting Angles	
X	-0.049 m	X	0.000 deg
Y	0.003 m	Y	0.000 deg
Z	-1.231 m	Z	0.000 deg
Standard Deviation			

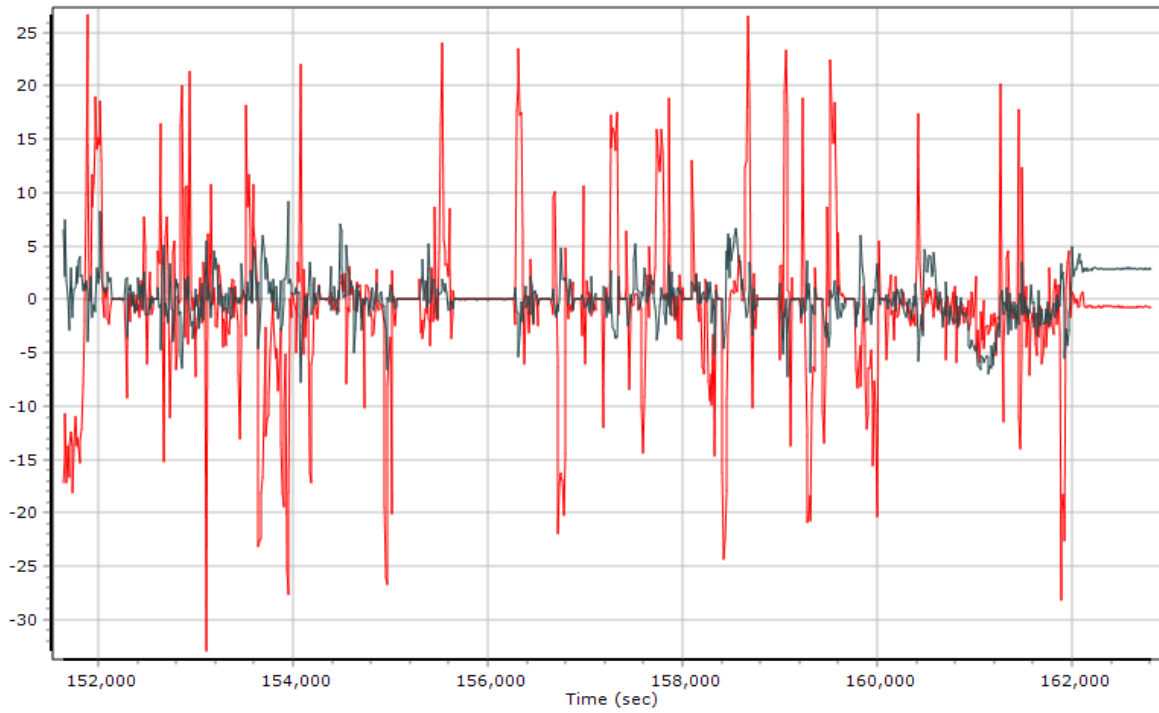
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

Timing

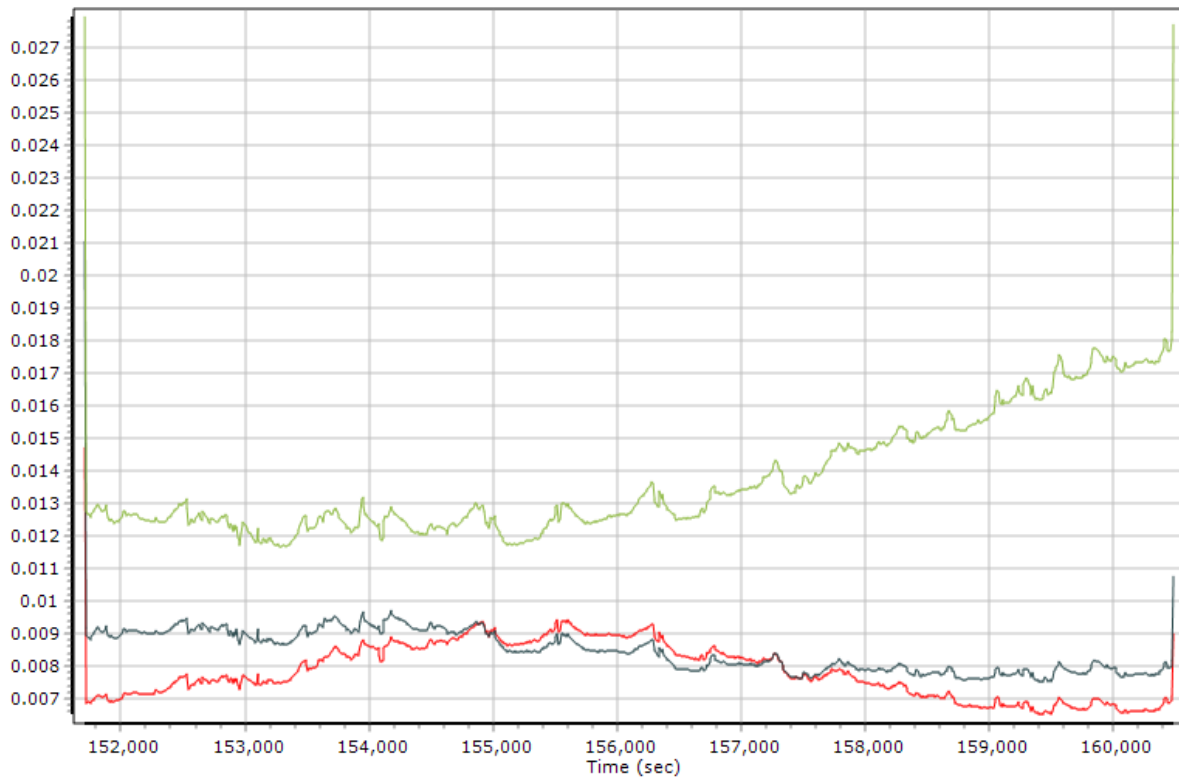
Start	151705.033	Data	Incr. (sec)
End	160484.088	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset

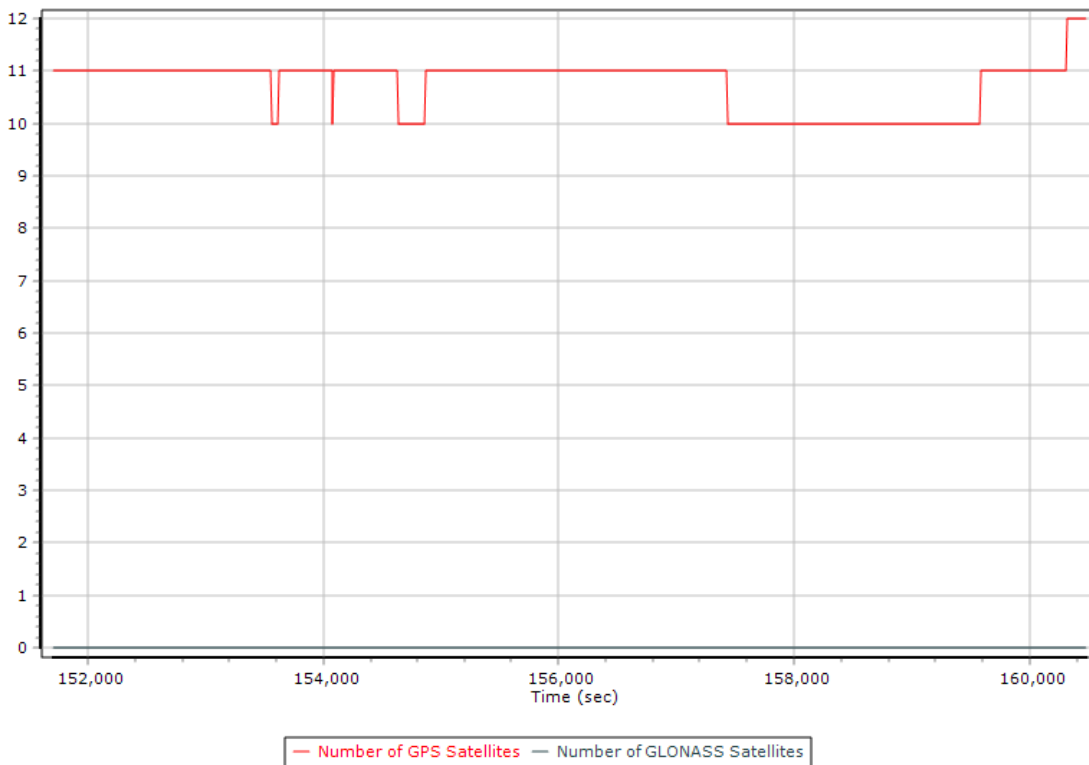
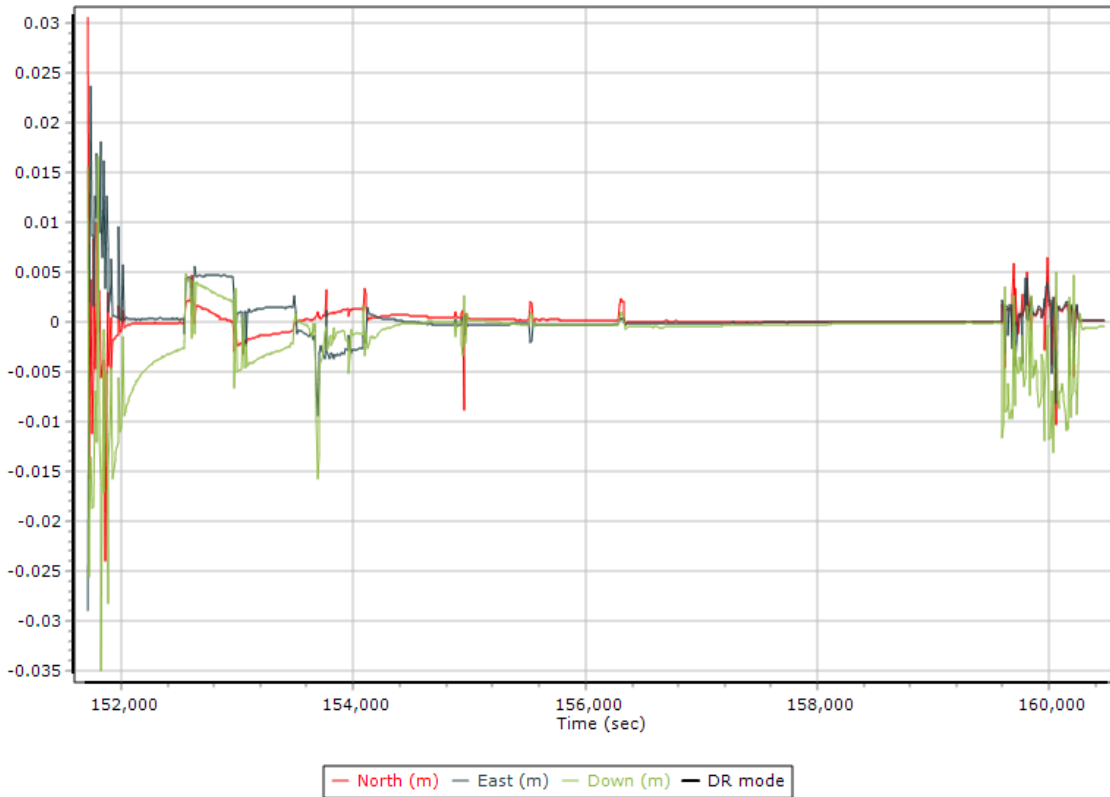


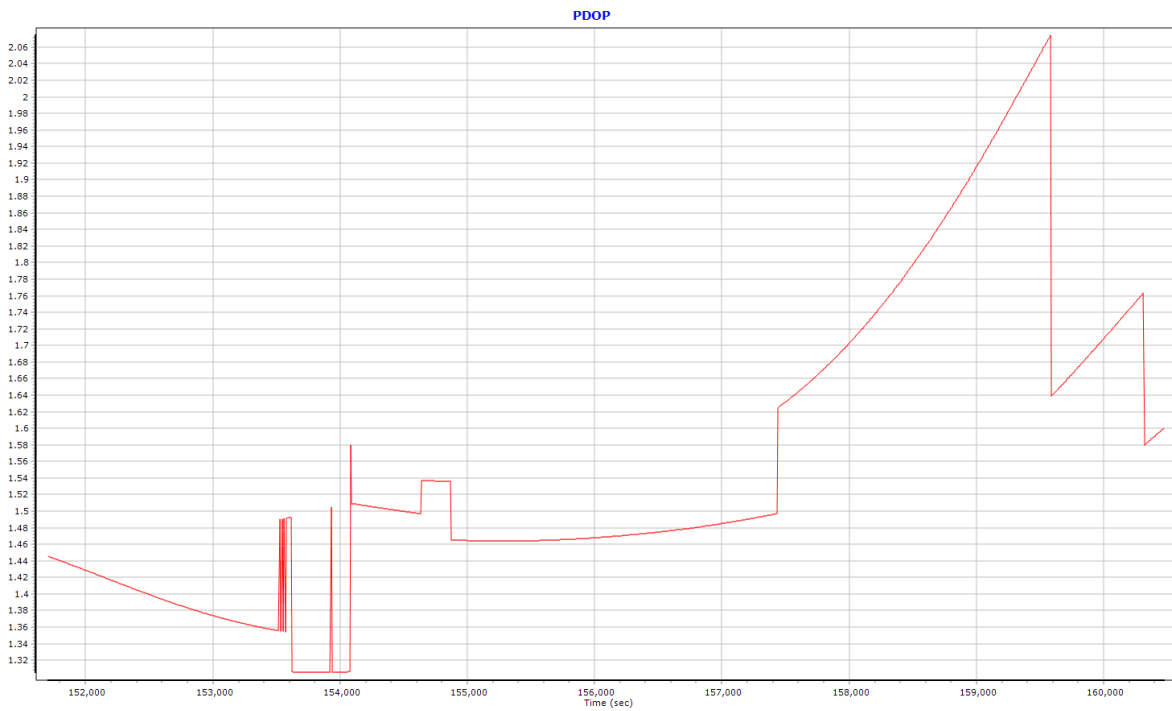
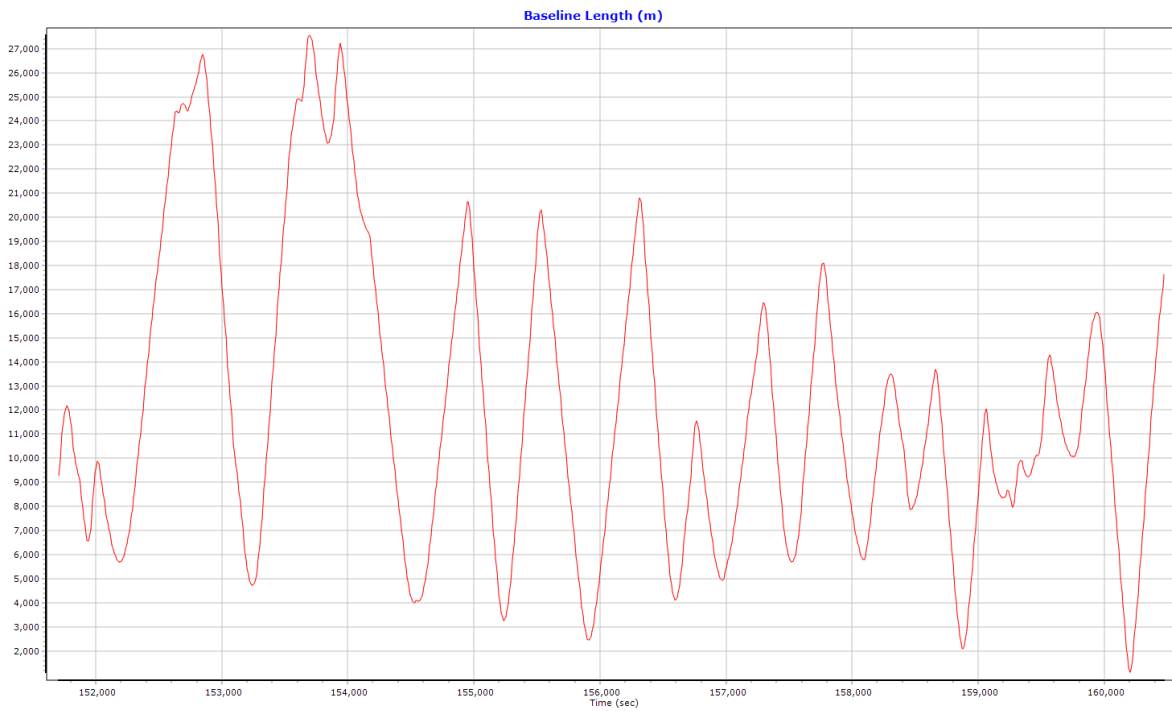


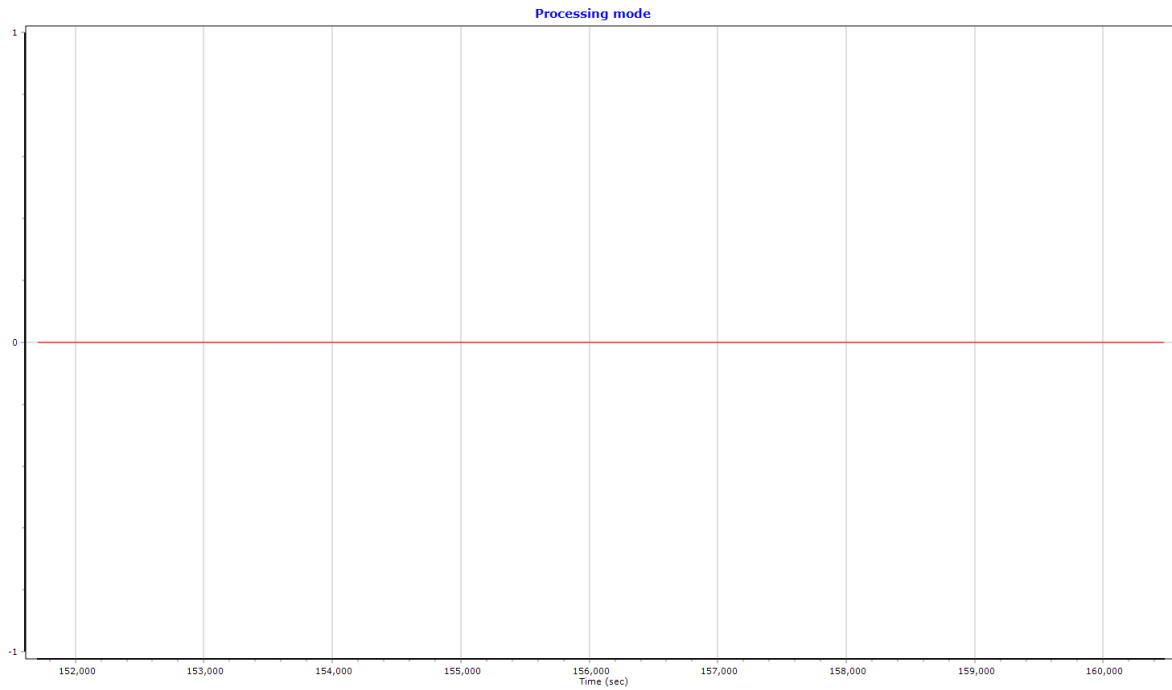
— Roll (deg) — Pitch (deg)



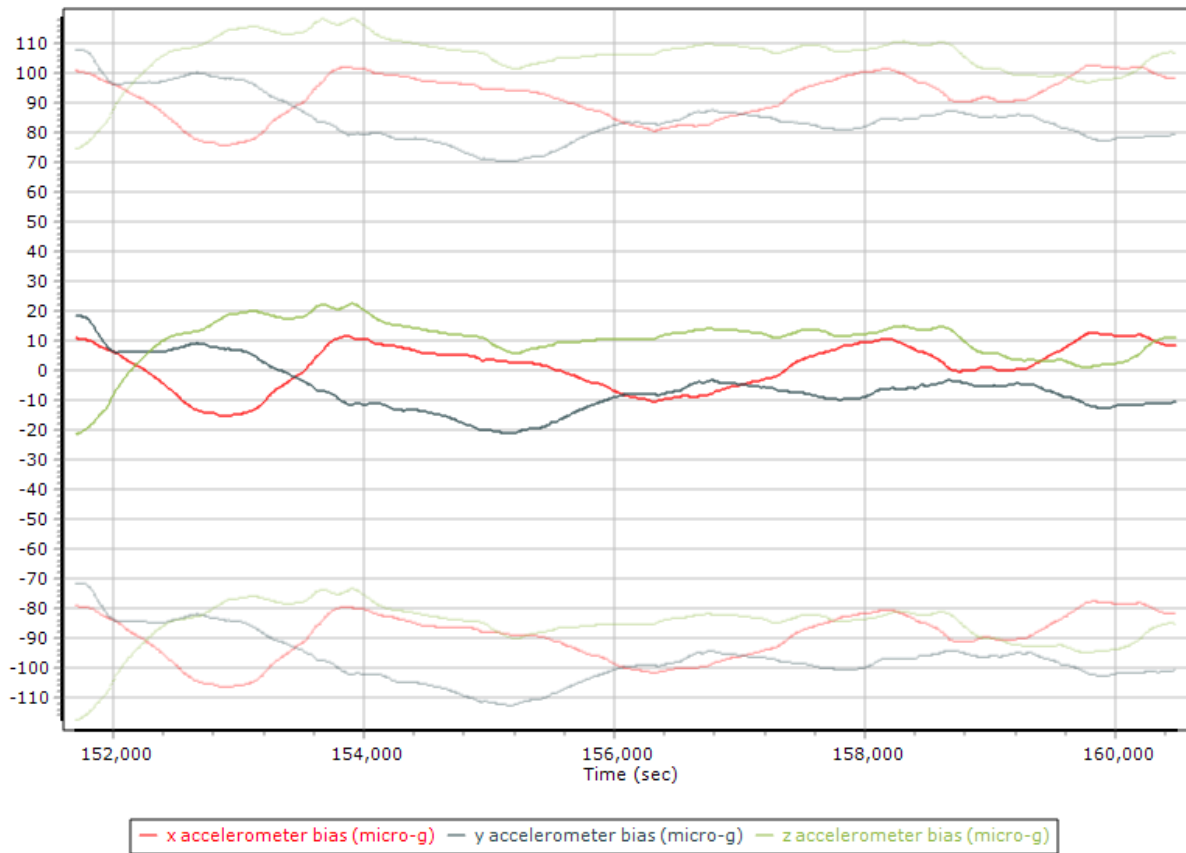
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)

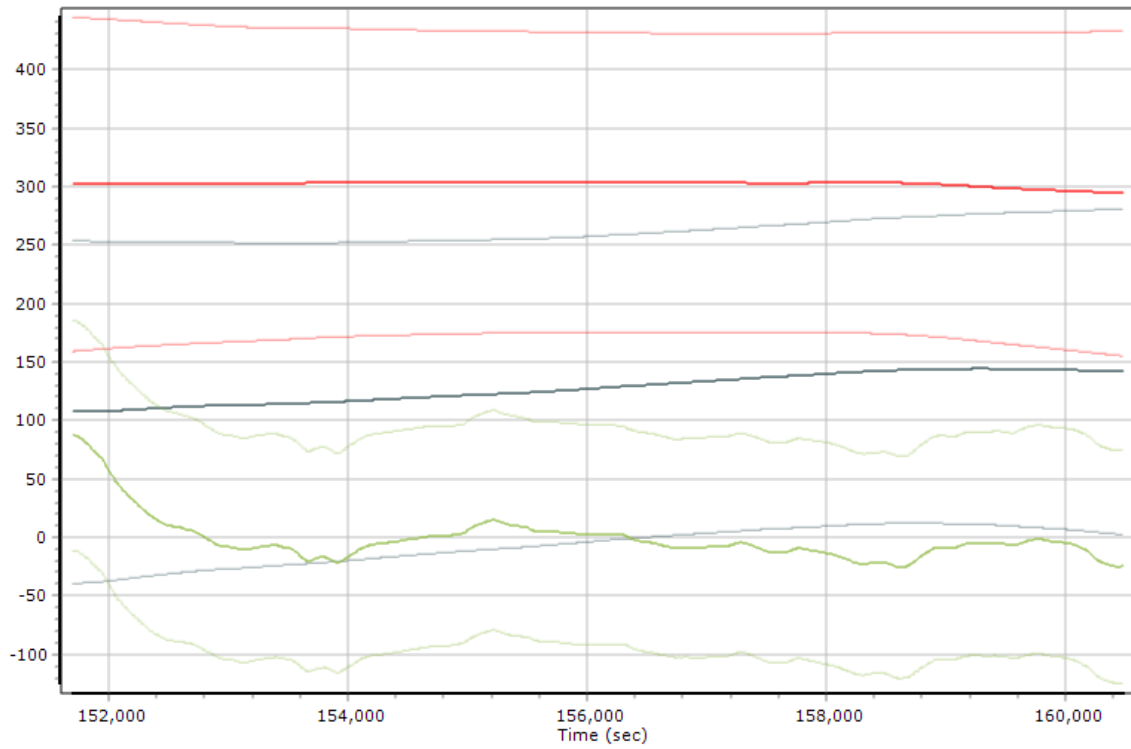




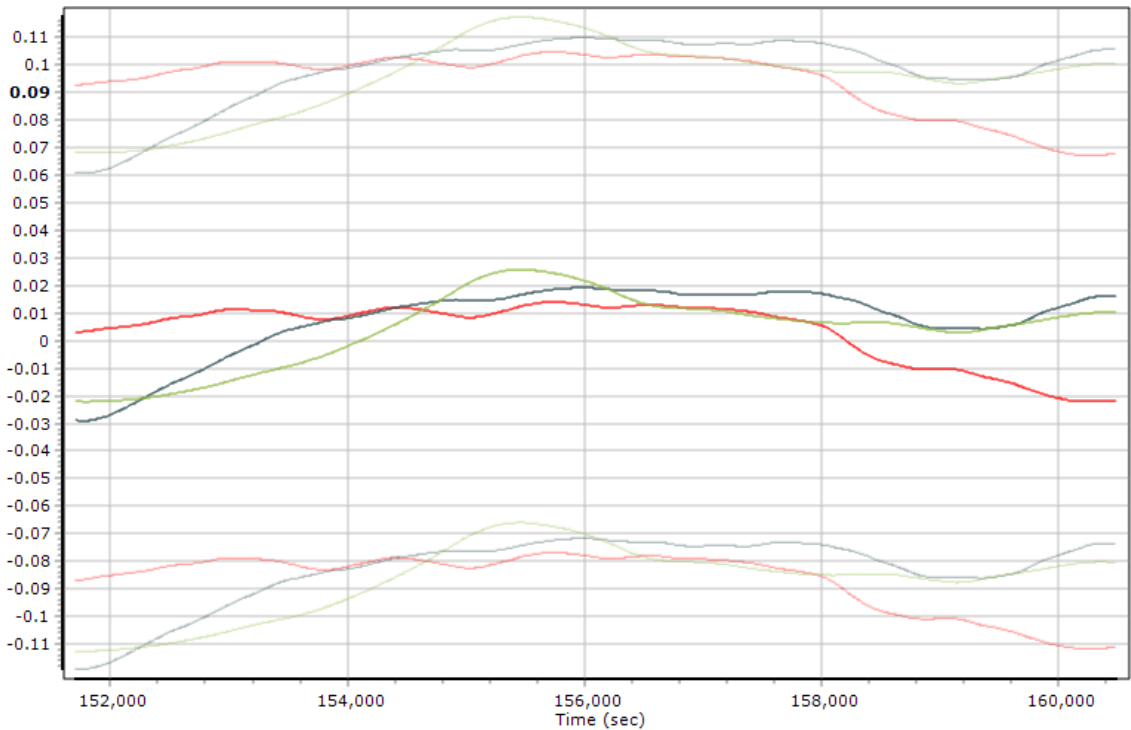


Sensor Errors

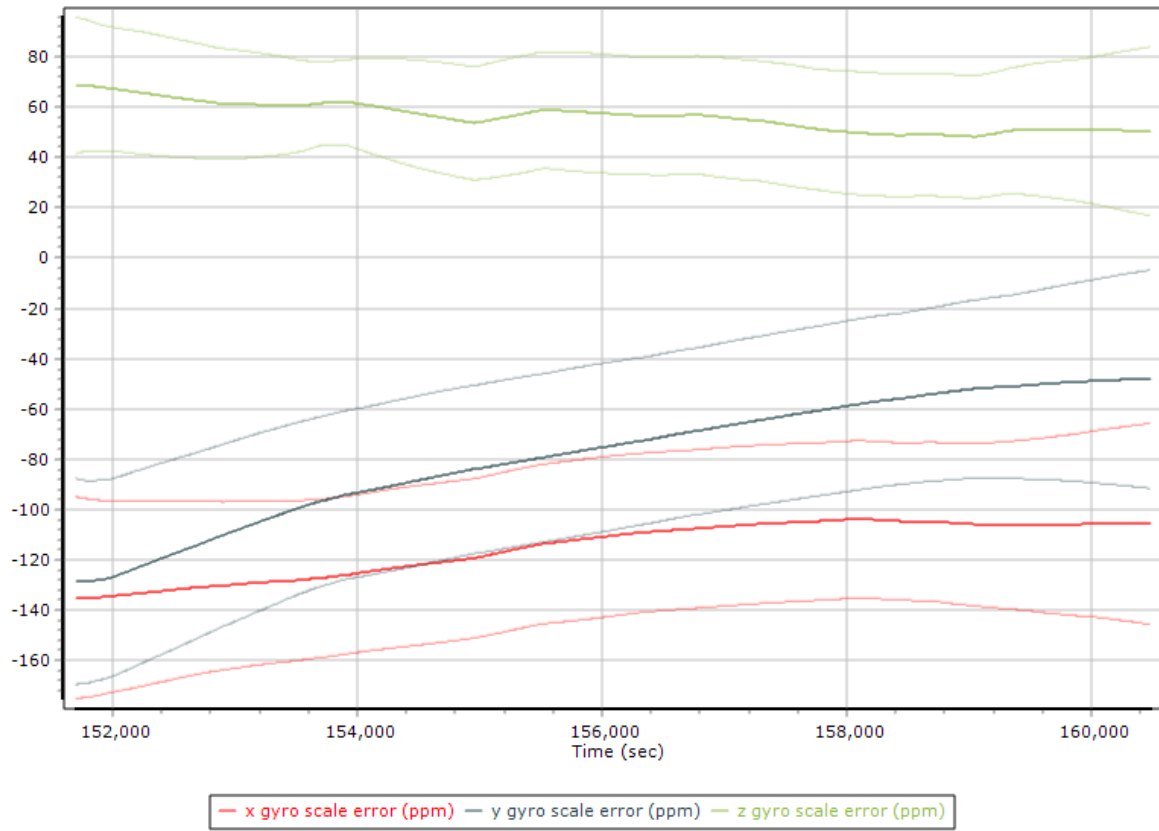




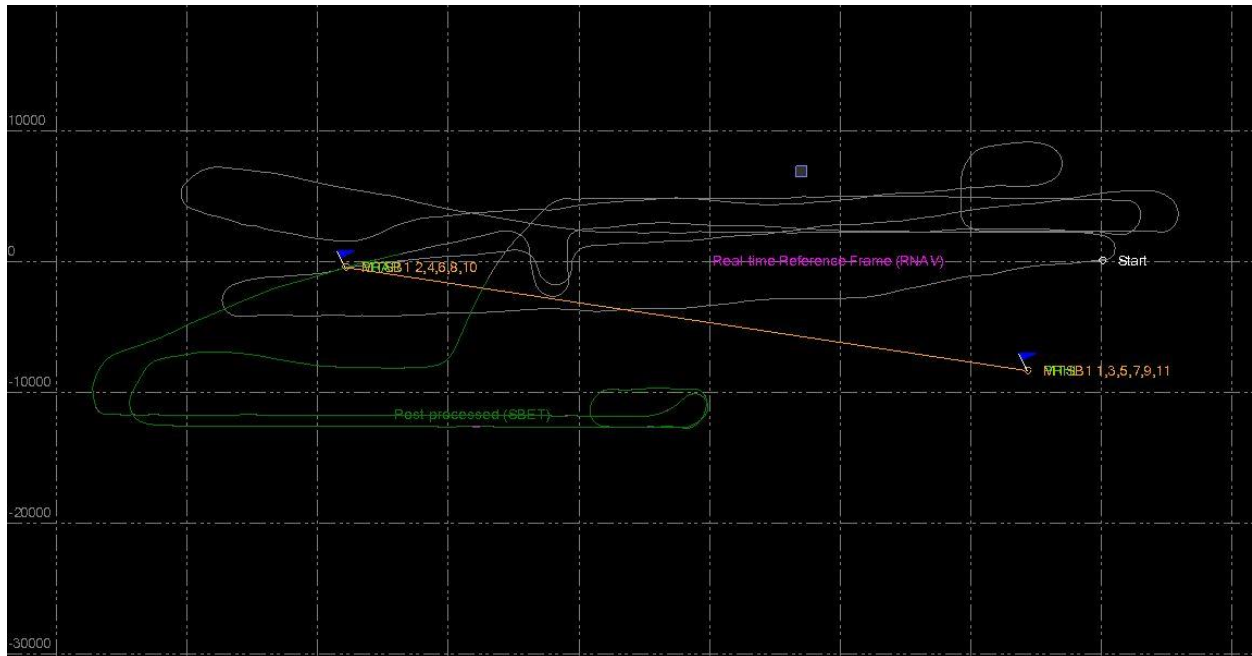
x accelerometer scale error (ppm) y accelerometer scale error (ppm) z accelerometer scale error (ppm)



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



AZT18127C1



Stabilized Mount to IMU Lever Arm

X:

Y:

Z:

Stabilized Mount to IMU Mounting Angles

X:

Y:

Z:

Stabilized Mount to Primary GNSS Lever Arm

X:

Y:

Z:

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

Aircraft to Stabilized Mount Mounting Angles

X:

Y:

Z:

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

Timing

Start:

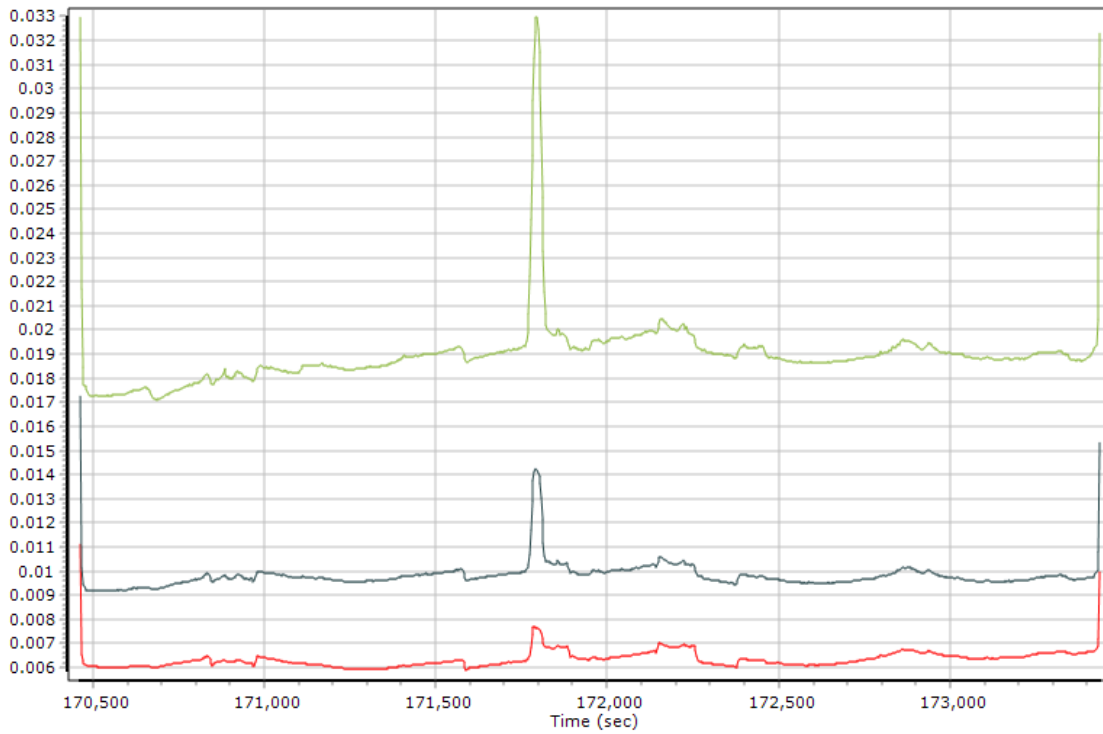
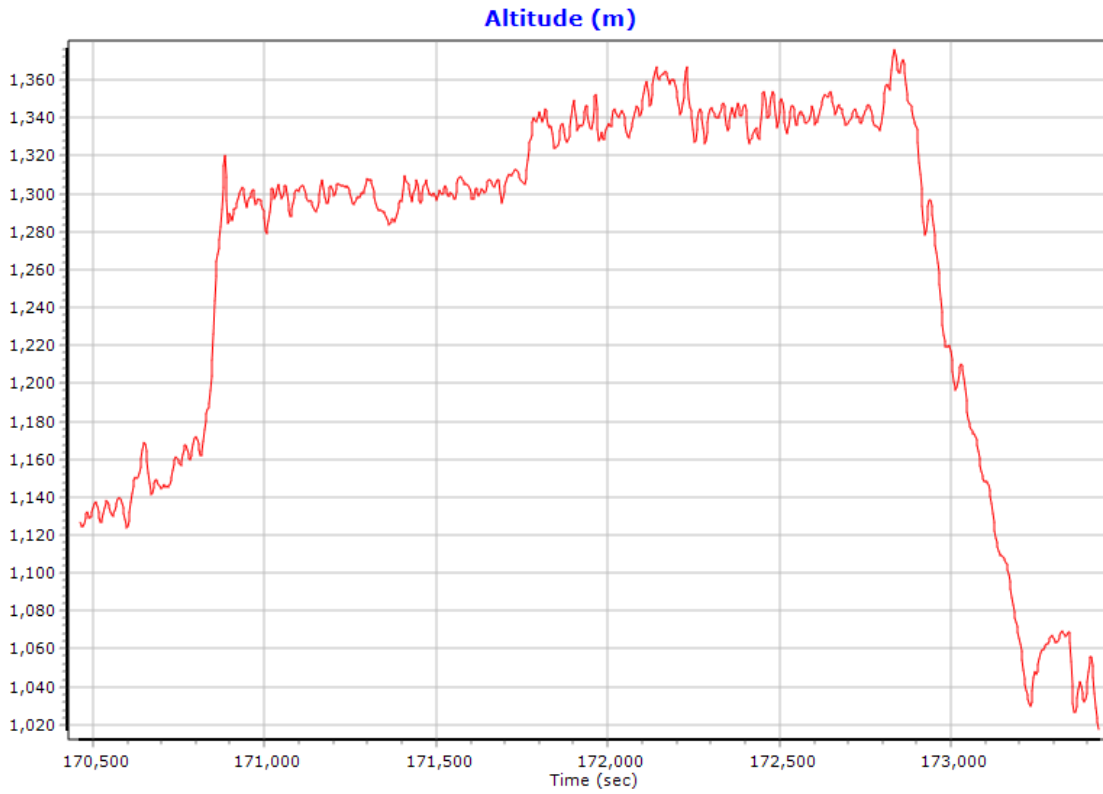
End:

Entire time interval

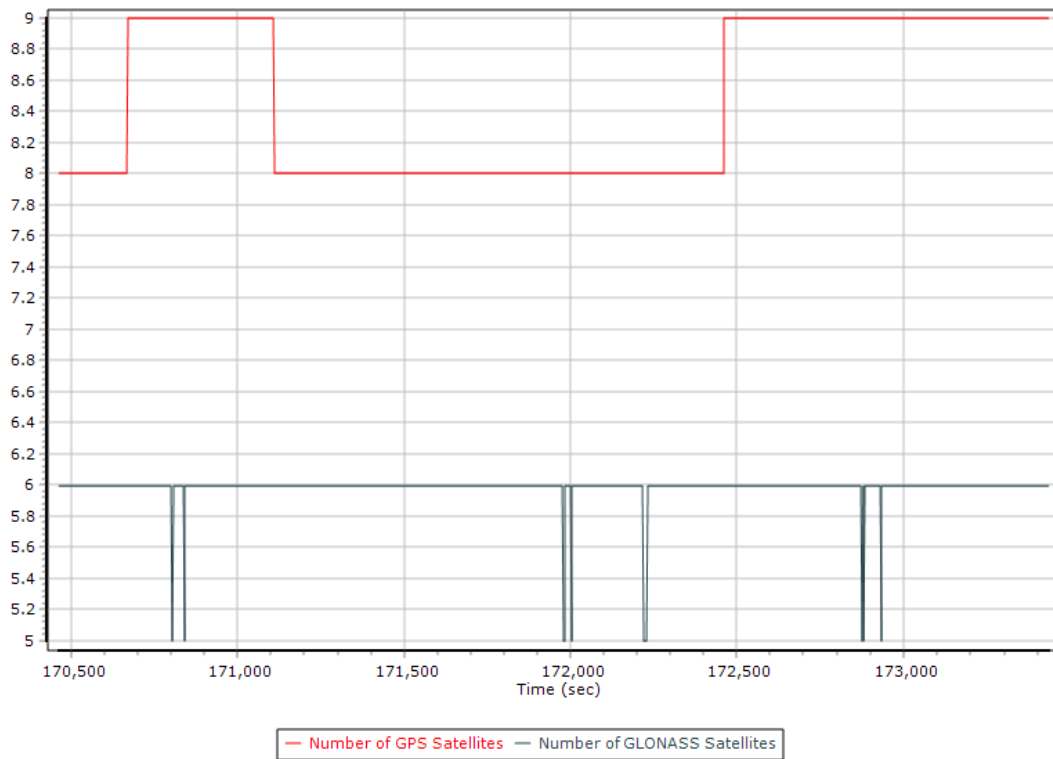
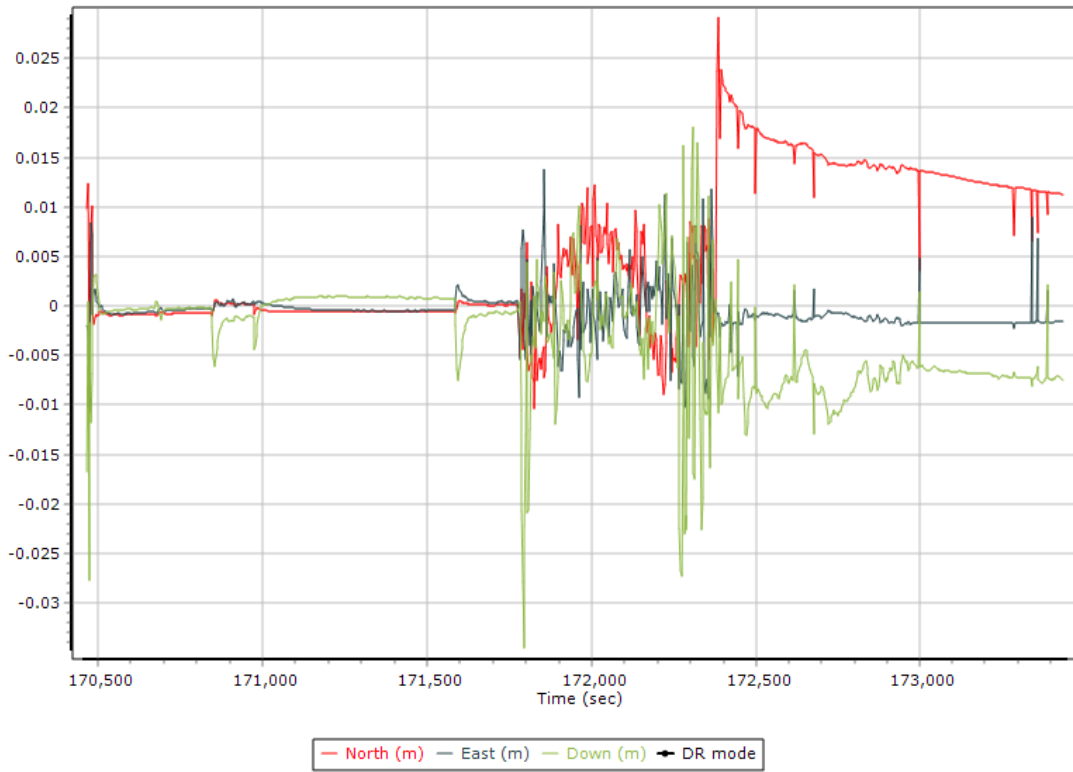
Seconds of start week

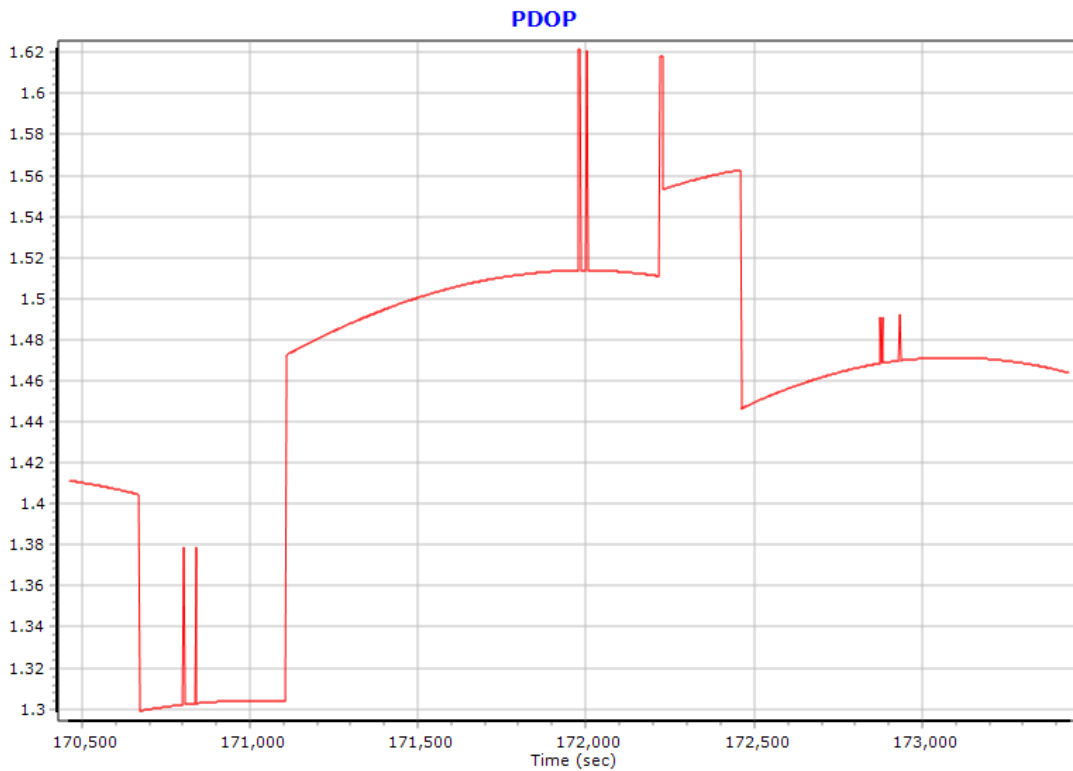
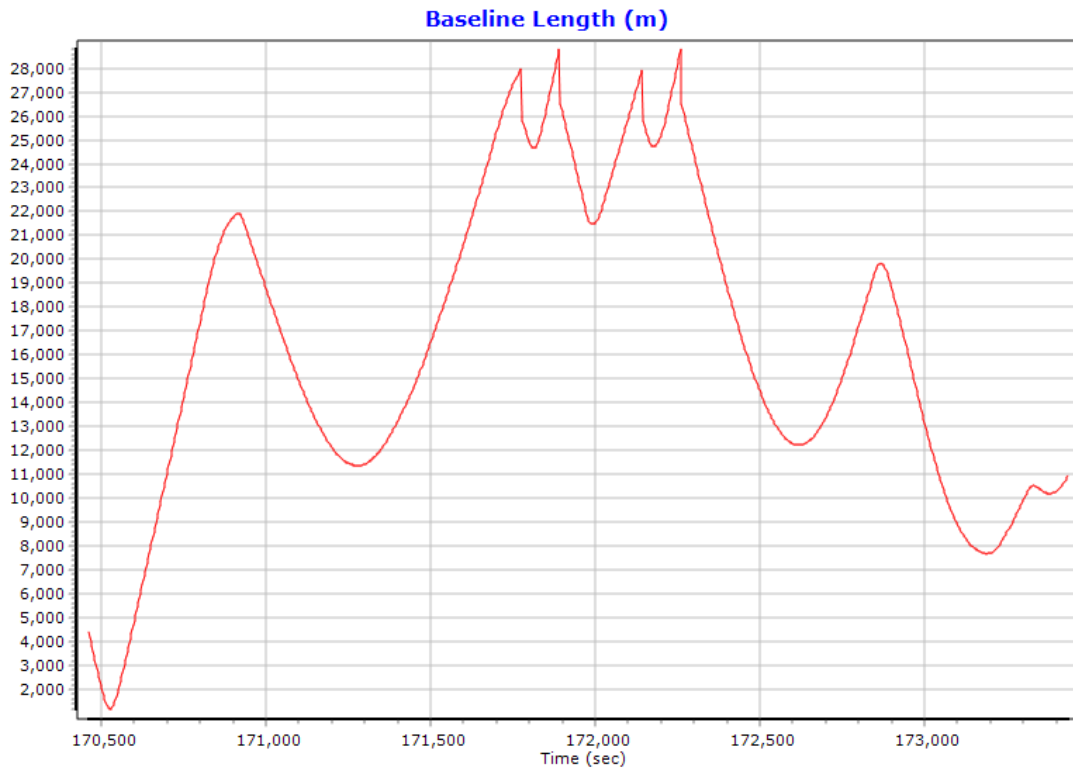
UTC Offset:

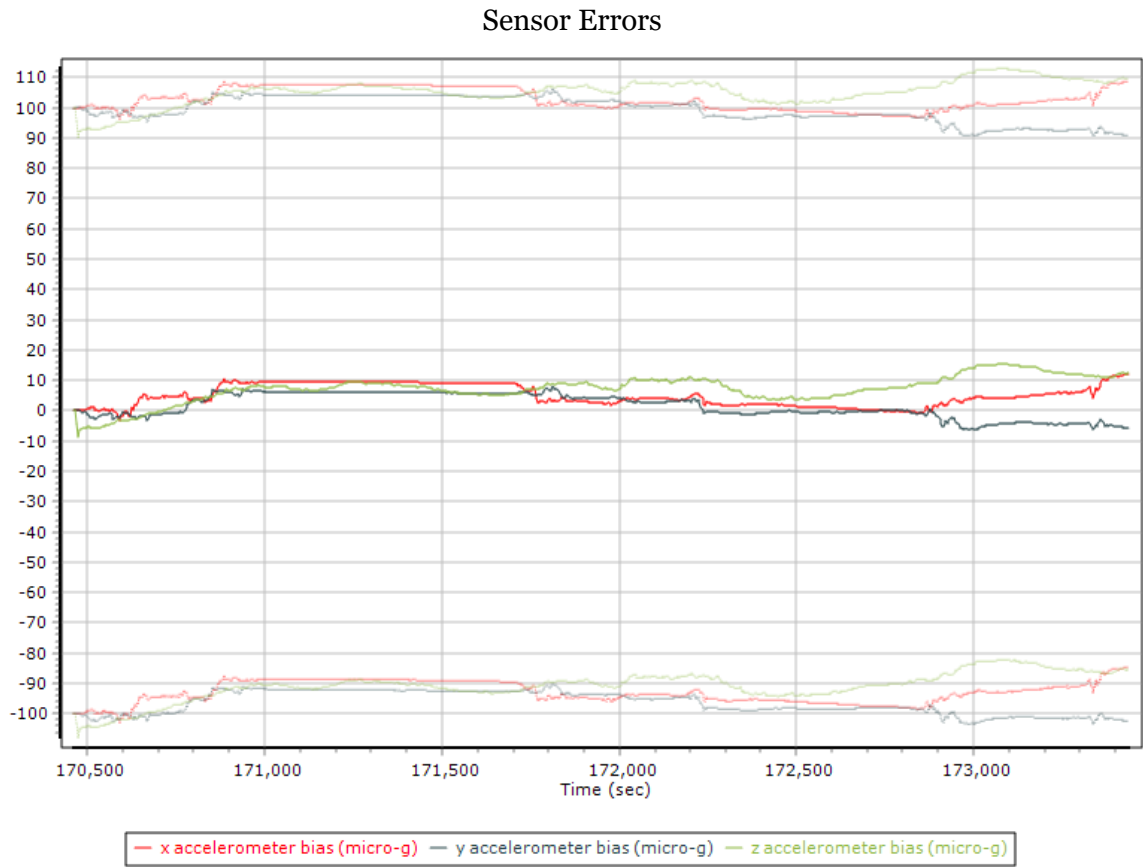
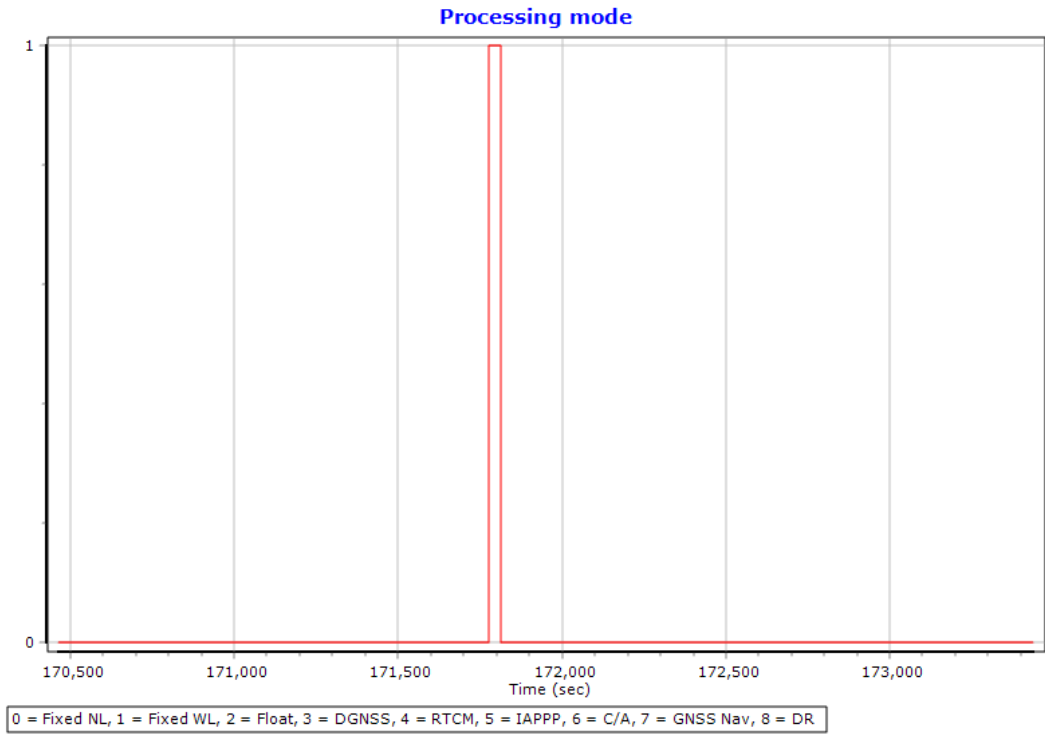
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

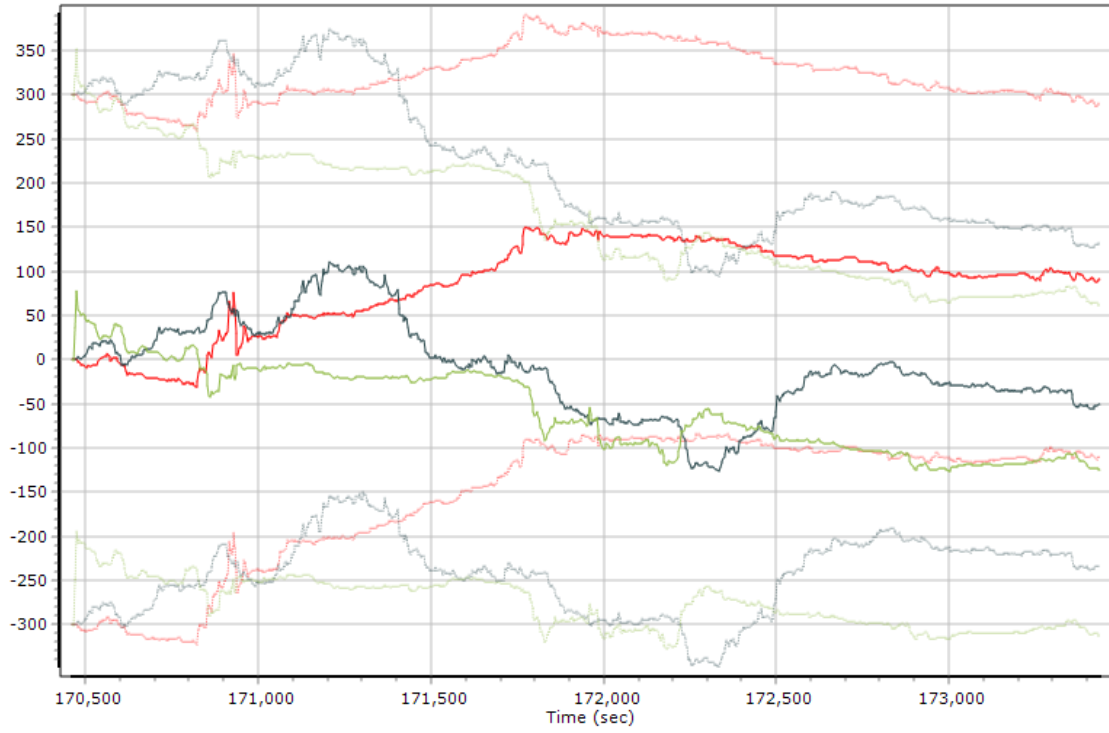


— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)

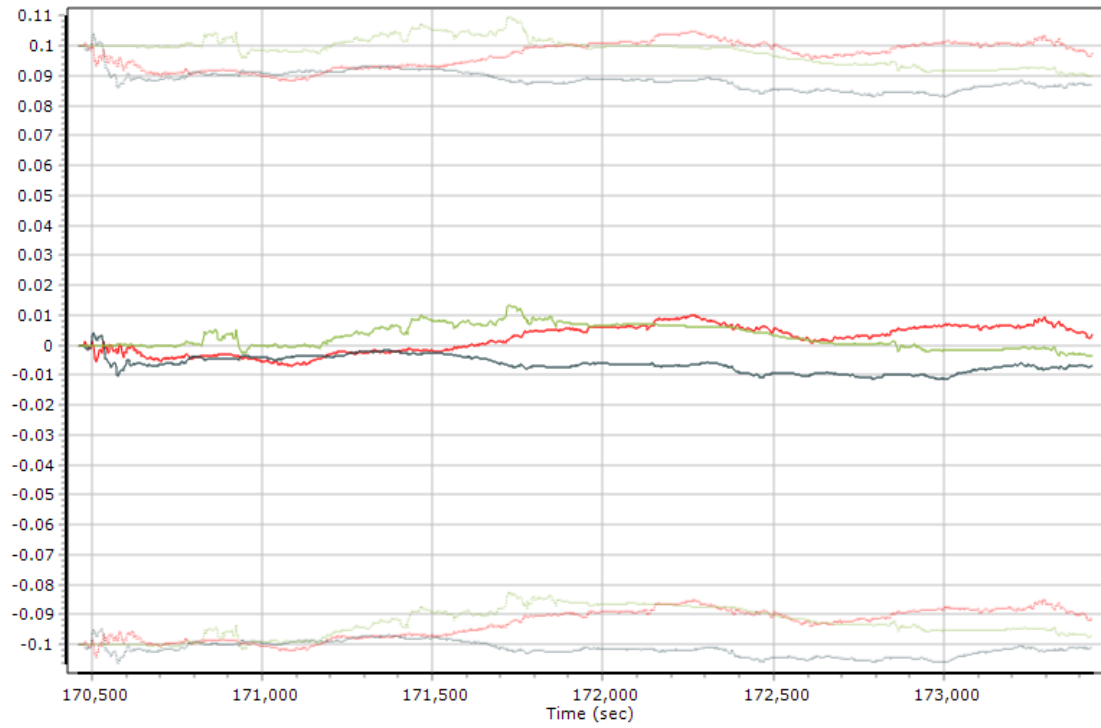




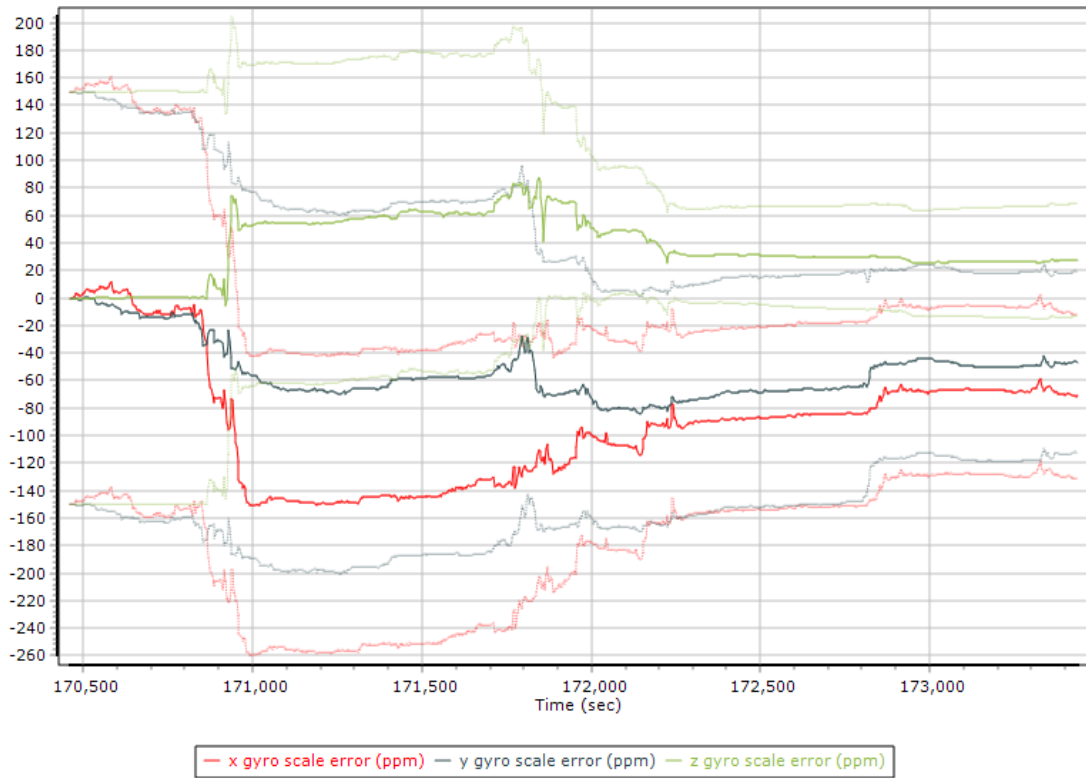




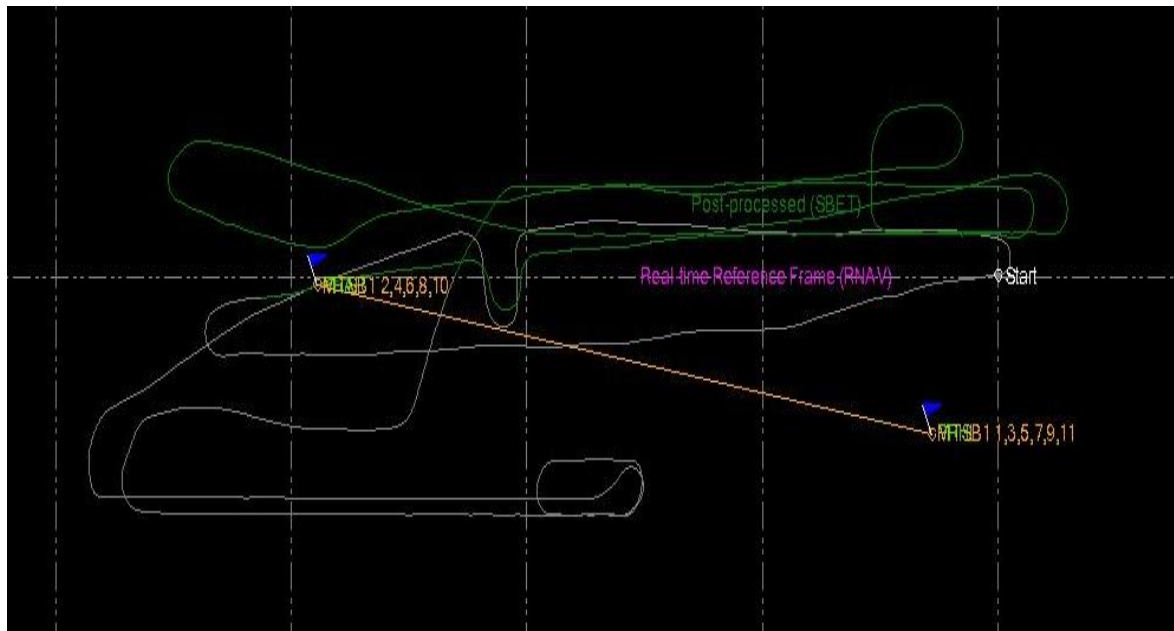
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

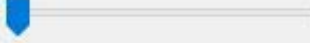


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



AZT18127C2



Stabilized Mount to IMU Lever Arm X: -0.034 m Y: -0.010 m Z: -0.352 m		Stabilized Mount to IMU Mounting Angles X: 0.000 deg Y: 0.000 deg Z: 0.000 deg	
Stabilized Mount to Primary GNSS Lever Arm X: -0.049 m Y: 0.003 m Z: -1.230 m Standard Deviation: 		Aircraft to Stabilized Mount Mounting Angles X: 0.000 deg Y: 0.000 deg Z: 0.000 deg	

<3cm 10cm 50cm 1m 10m

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

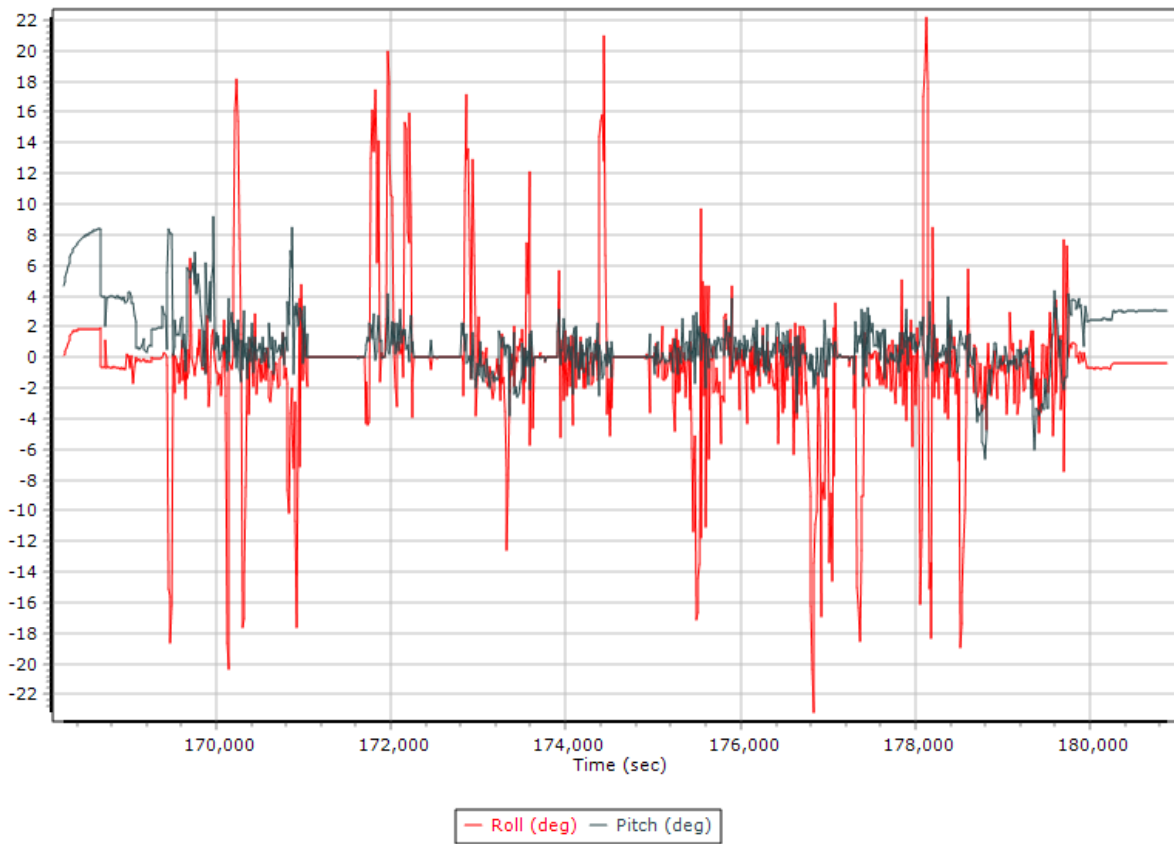
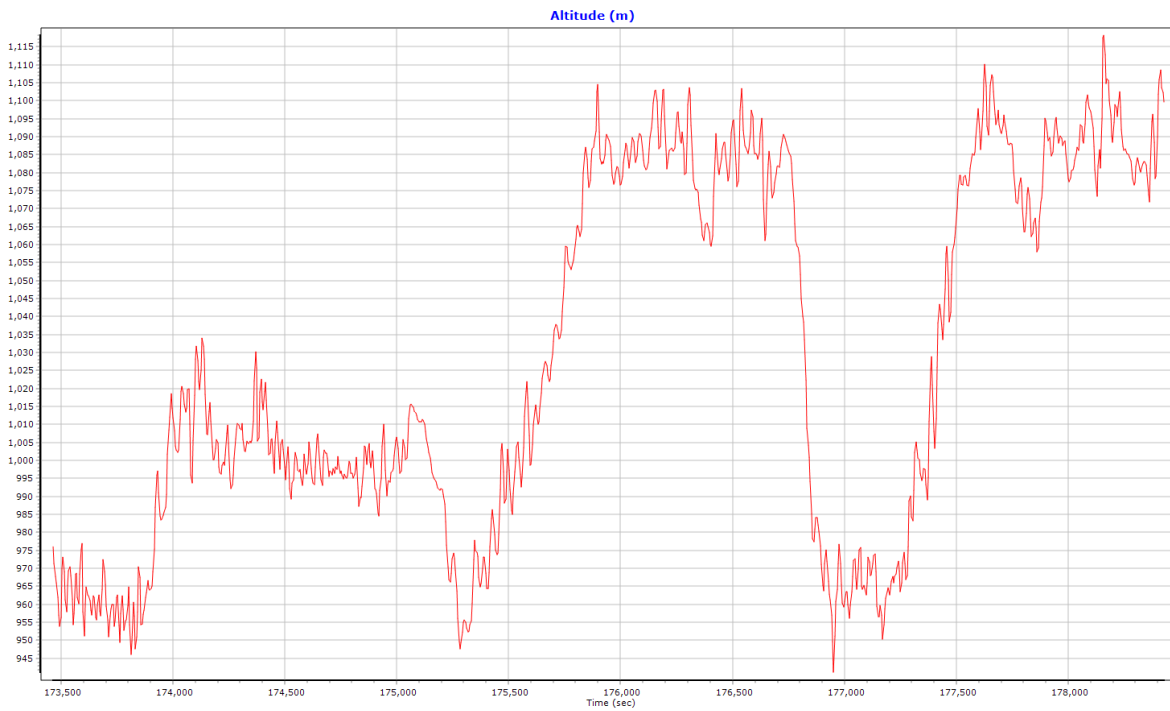
Timing

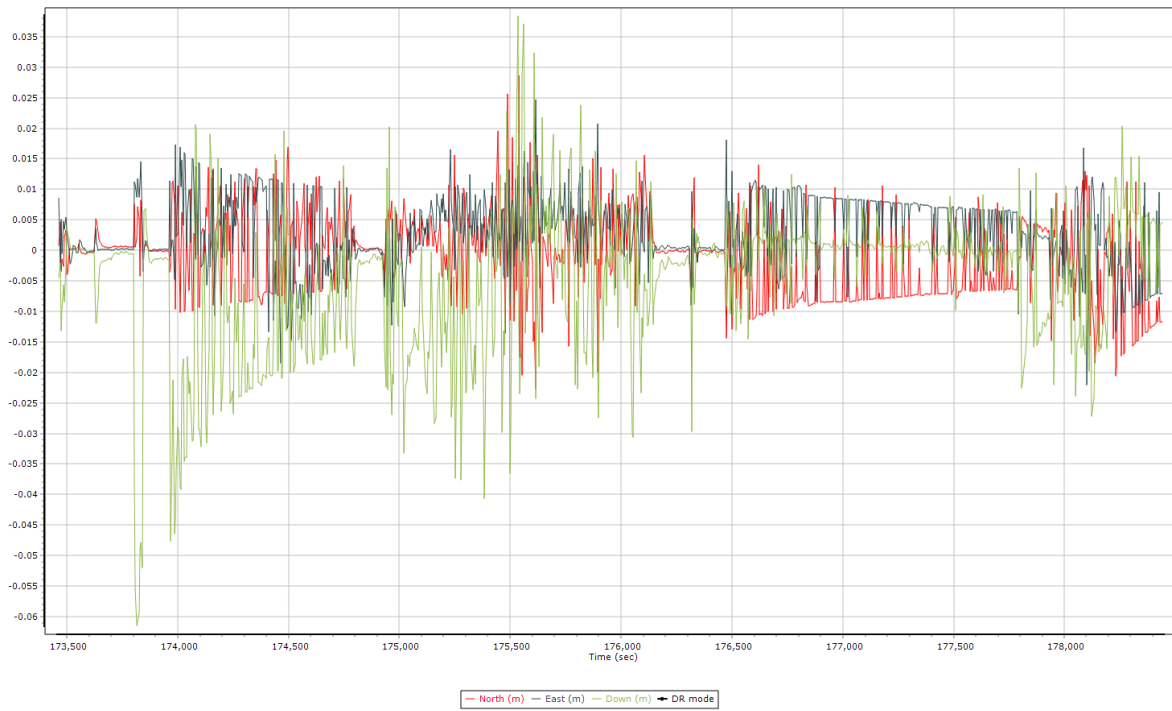
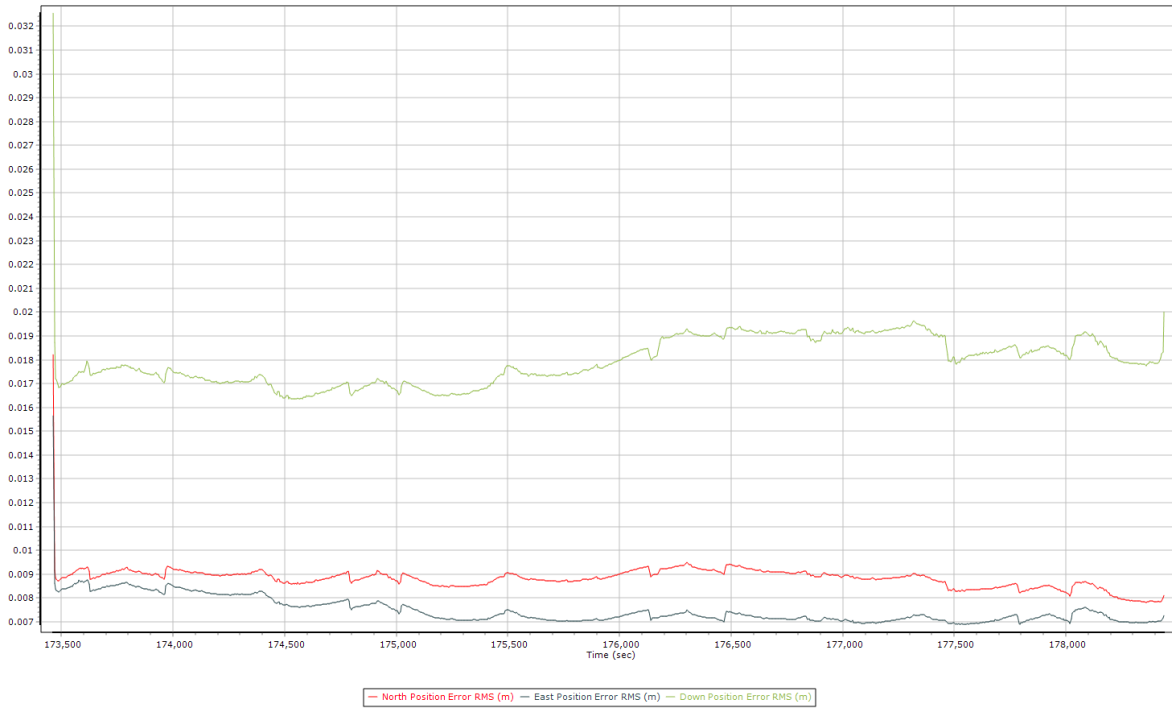
Start: 173461.214
 End: 178445.375

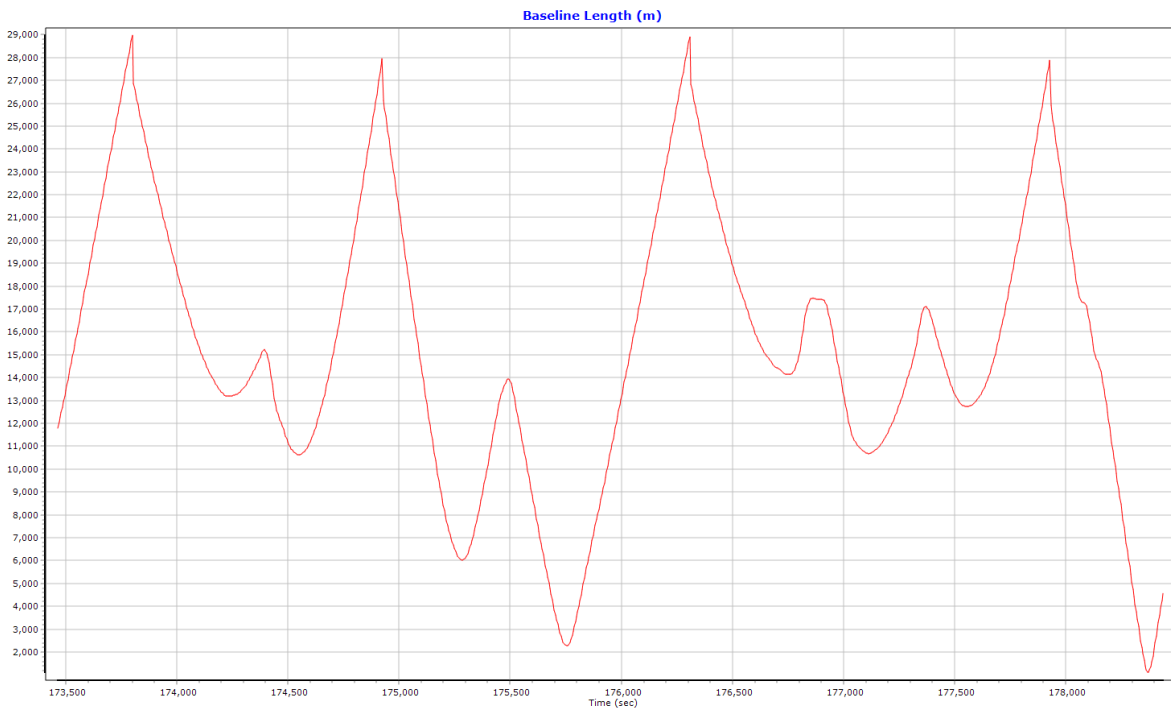
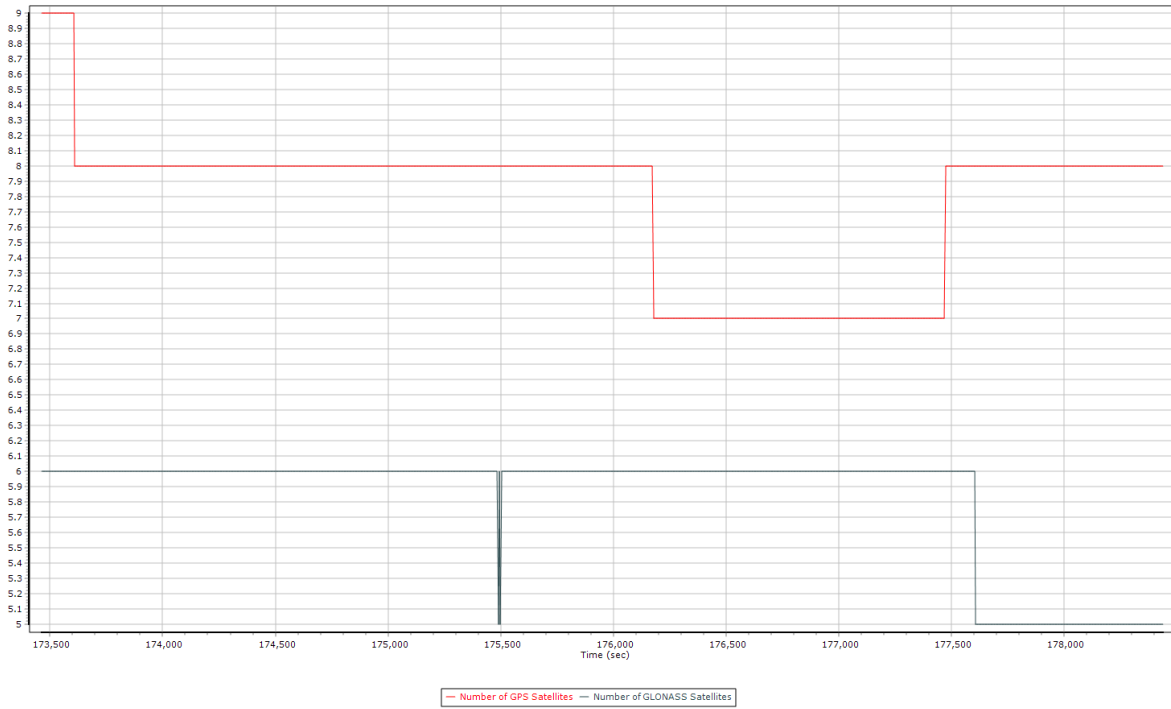
Entire time interval
 Seconds of start week

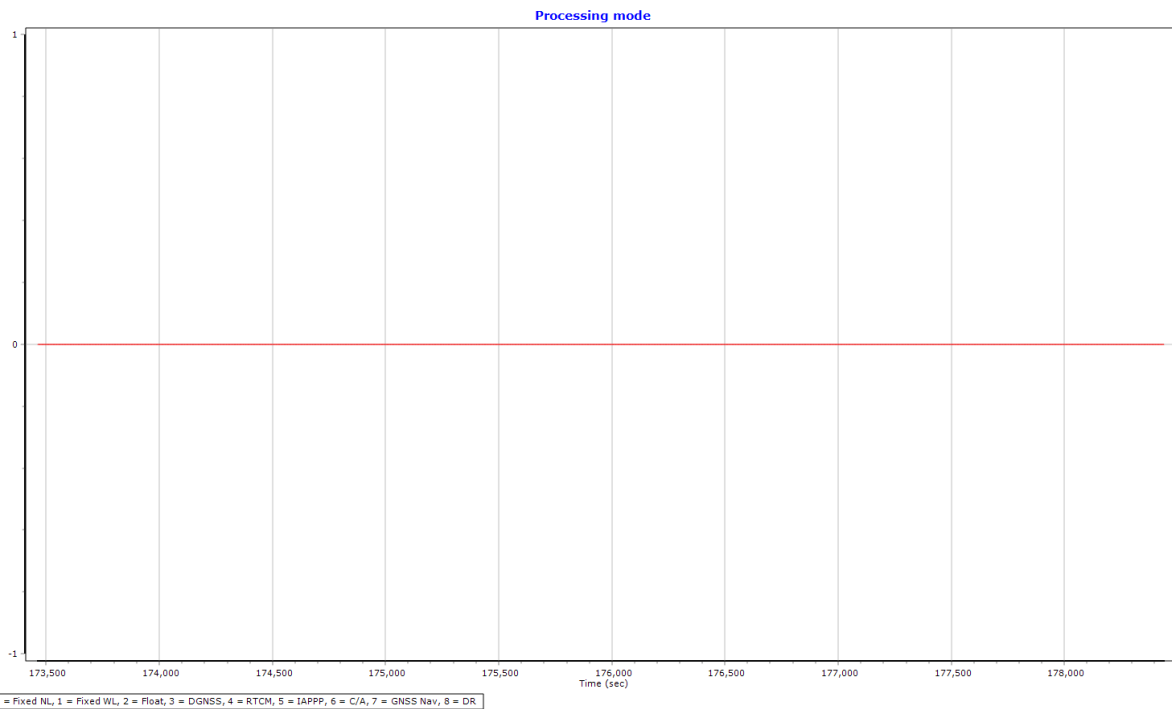
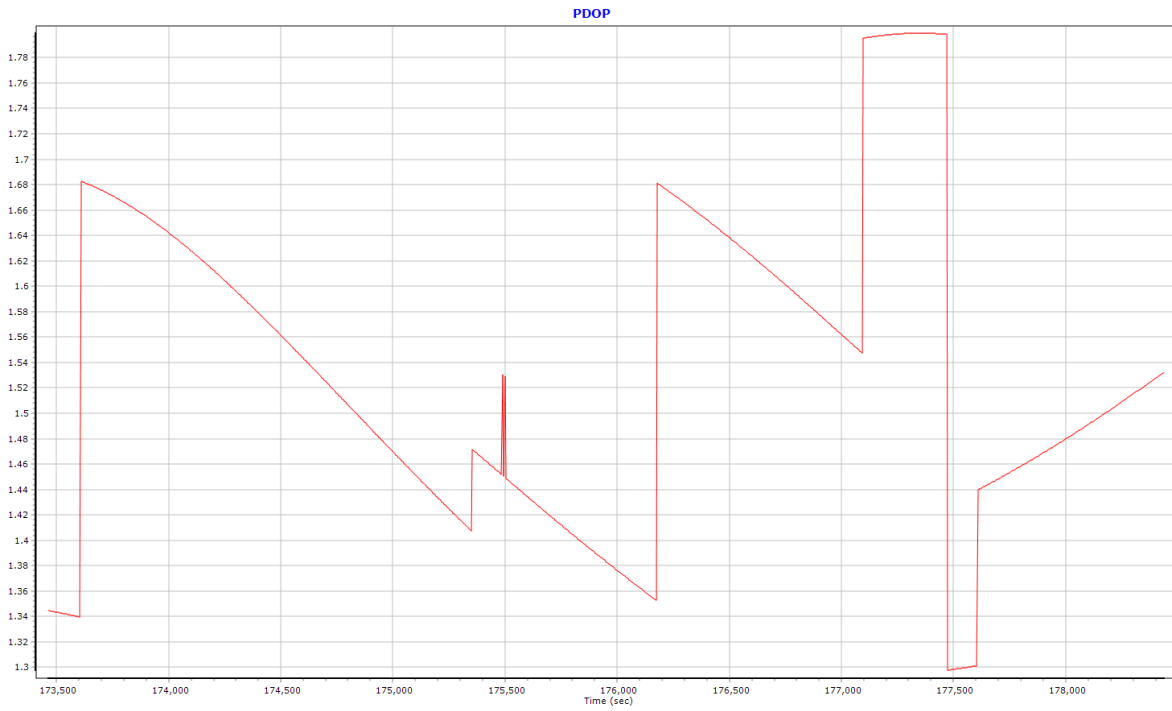
UTC Offset: 18.000

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

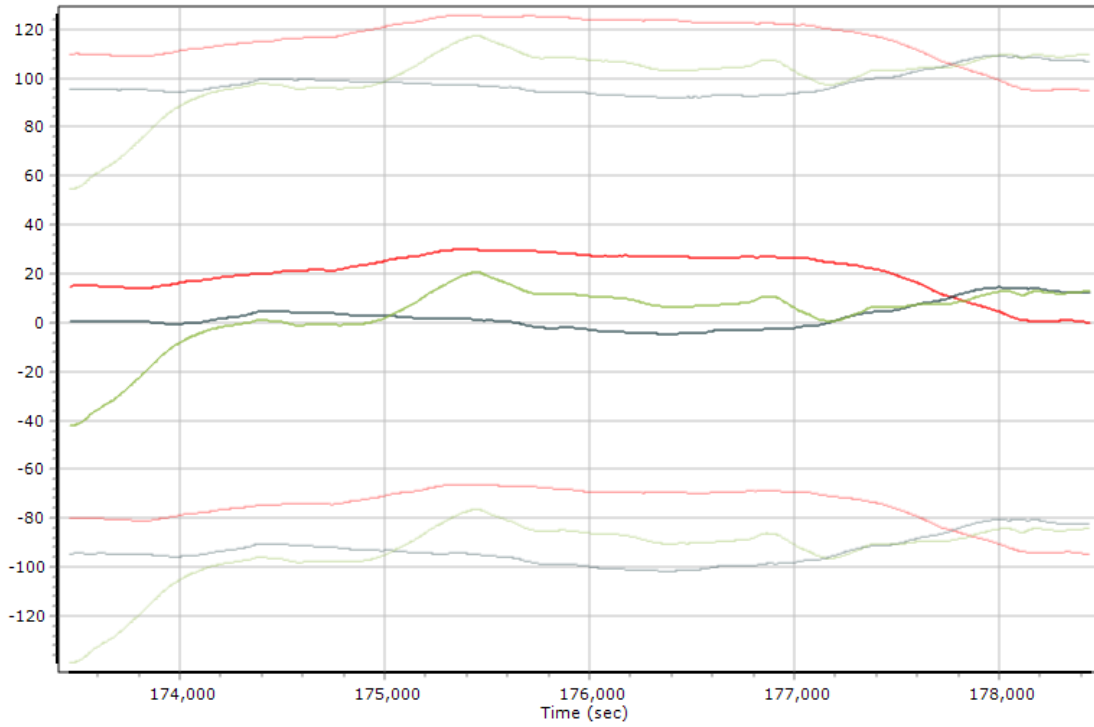




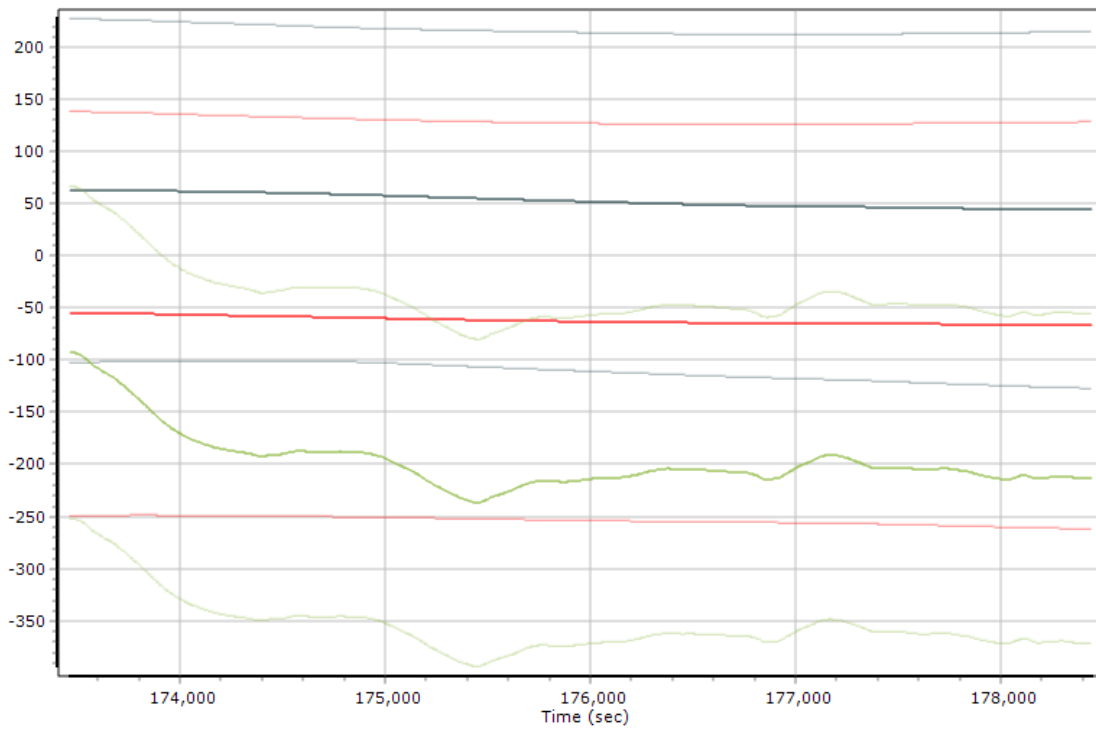




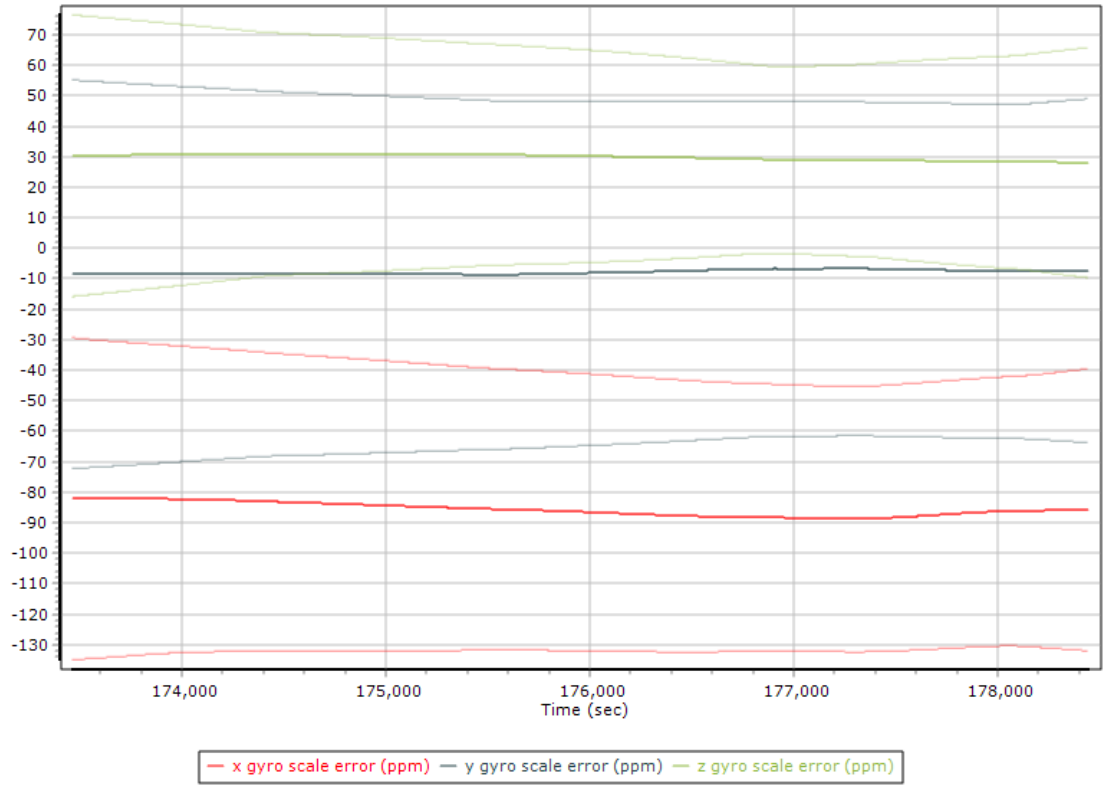
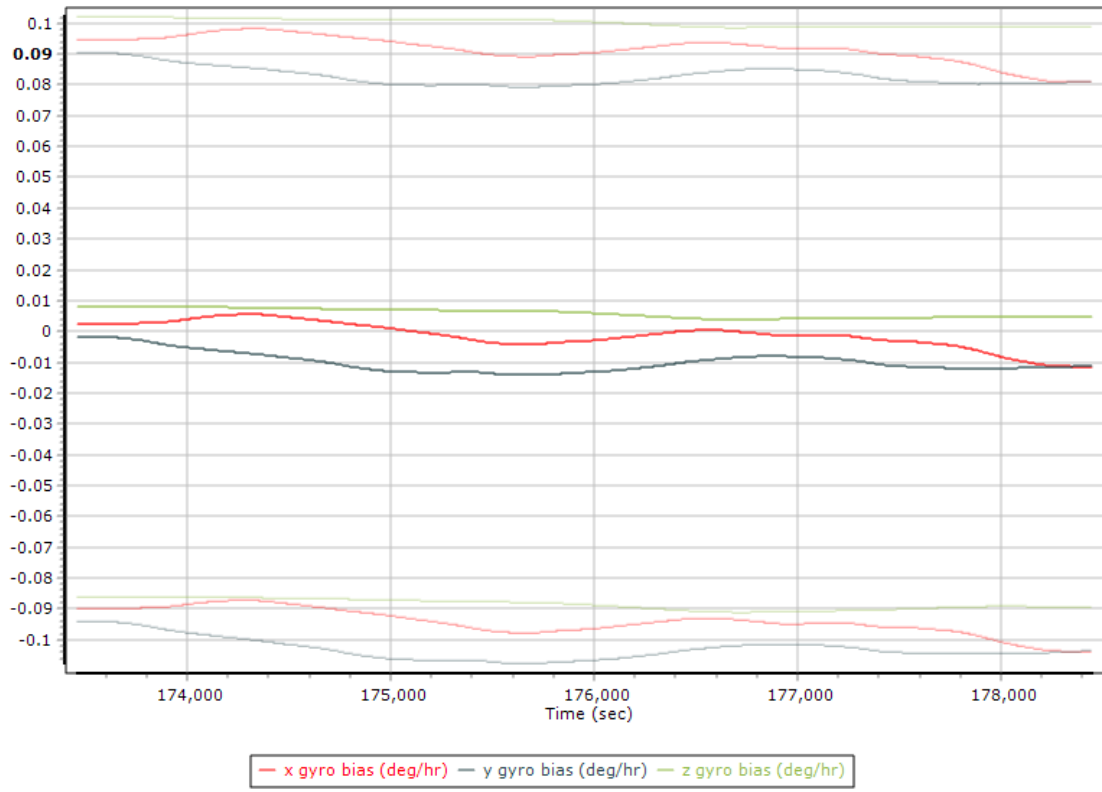
Sensor Errors



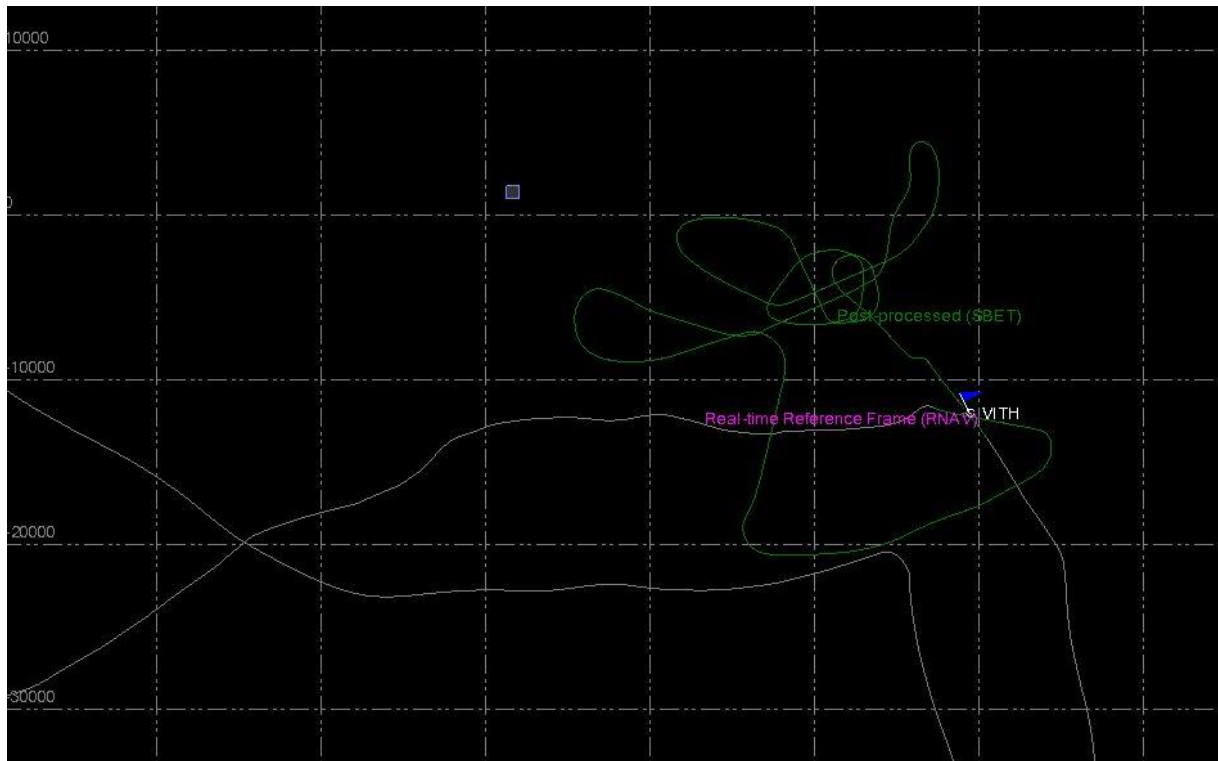
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



AZT18128A1



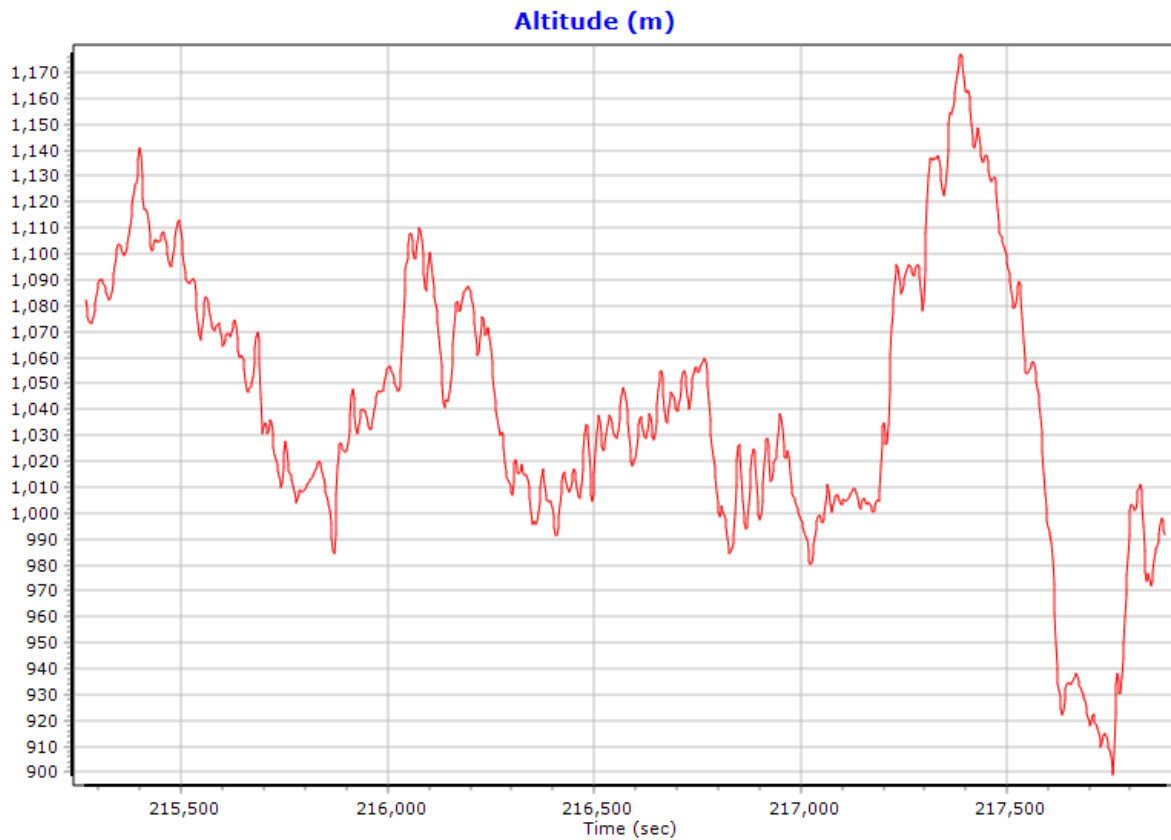
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	-0.034 m	X	0.000 deg
Y	-0.010 m	Y	0.000 deg
Z	-0.352 m	Z	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm		Aircraft to Stabilized Mount Mounting Angles	
X	-0.049 m	X	0.000 deg
Y	0.003 m	Y	0.000 deg
Z	-1.230 m	Z	0.000 deg
Standard Deviation			

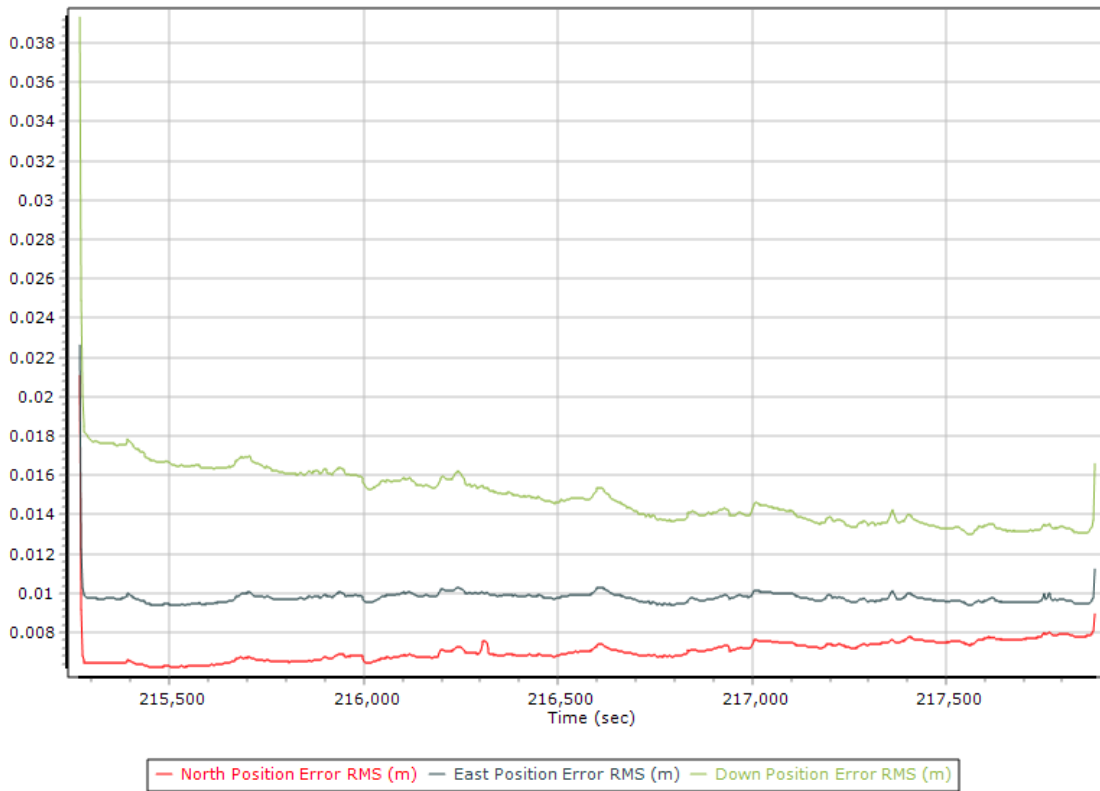
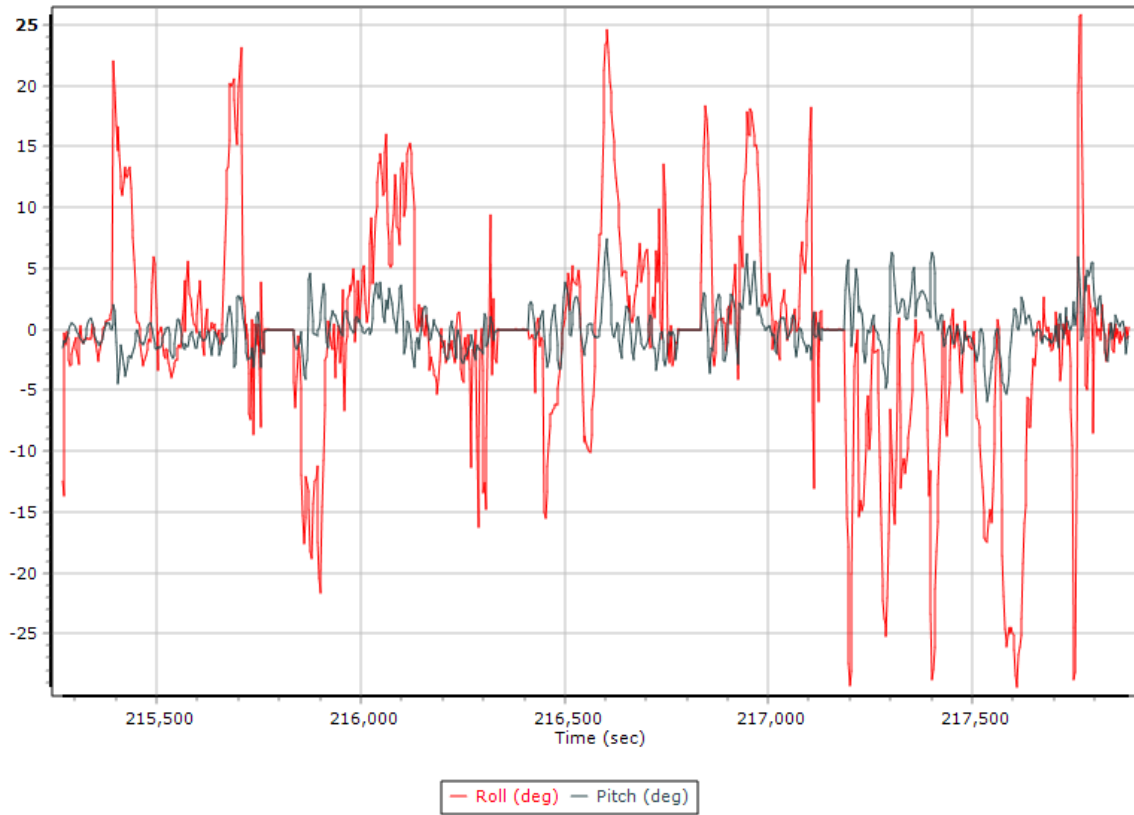
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

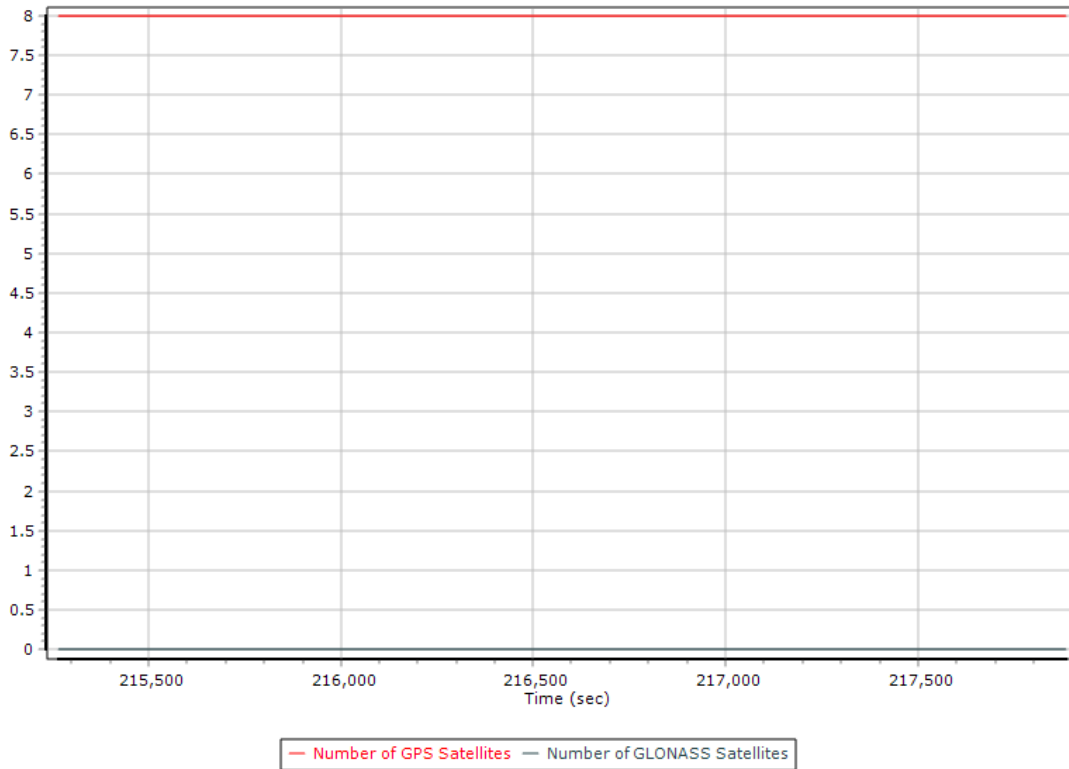
Timing

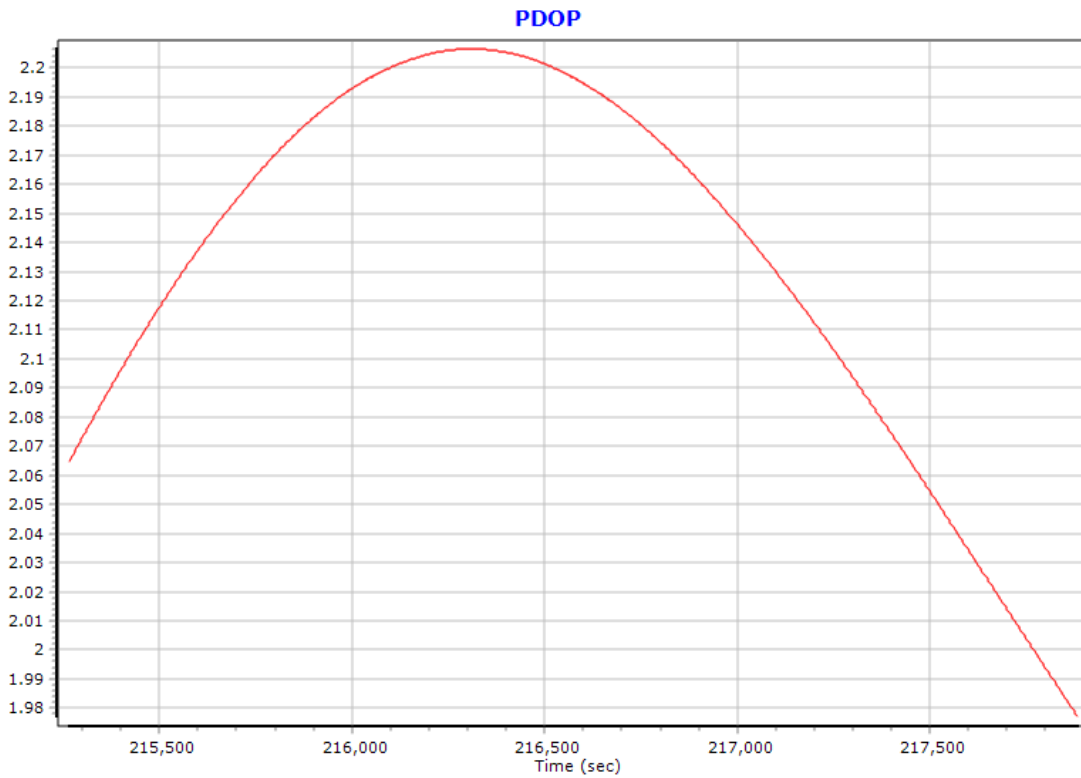
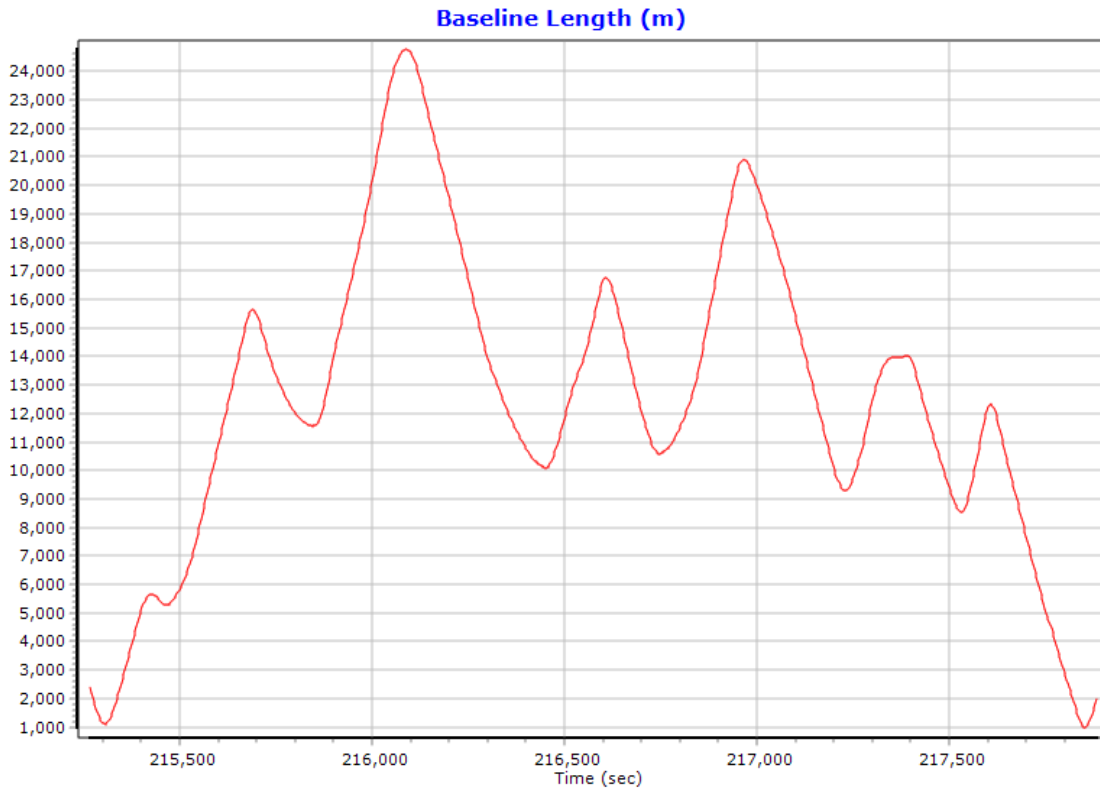
Start	215265.823	Data	Incr. (sec)
End	217885.431	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset

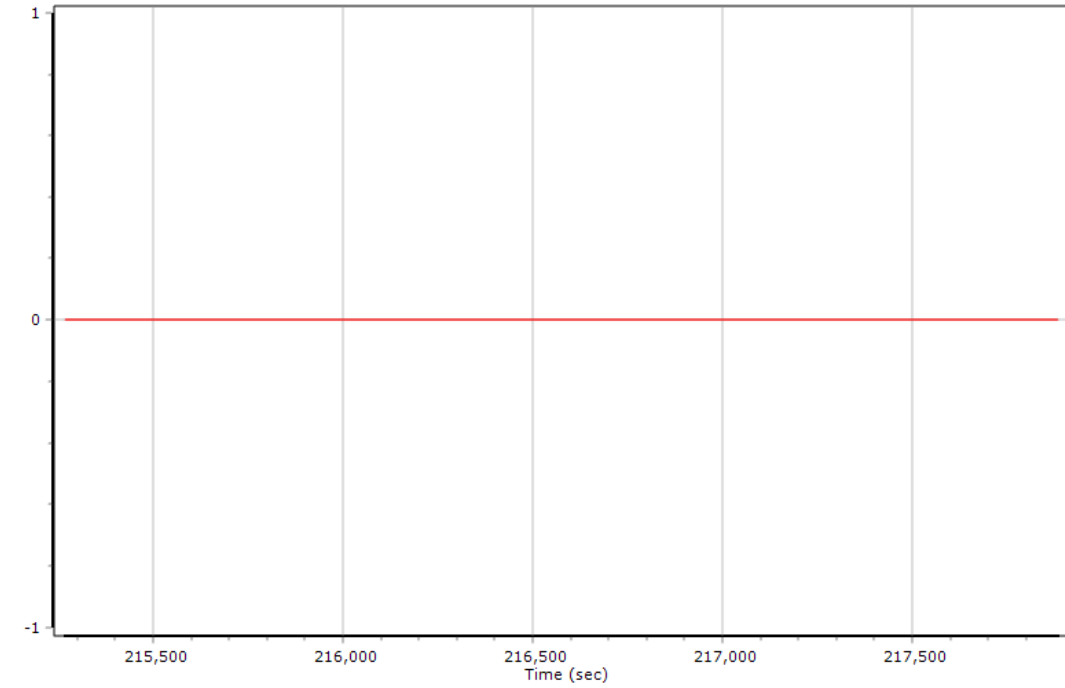






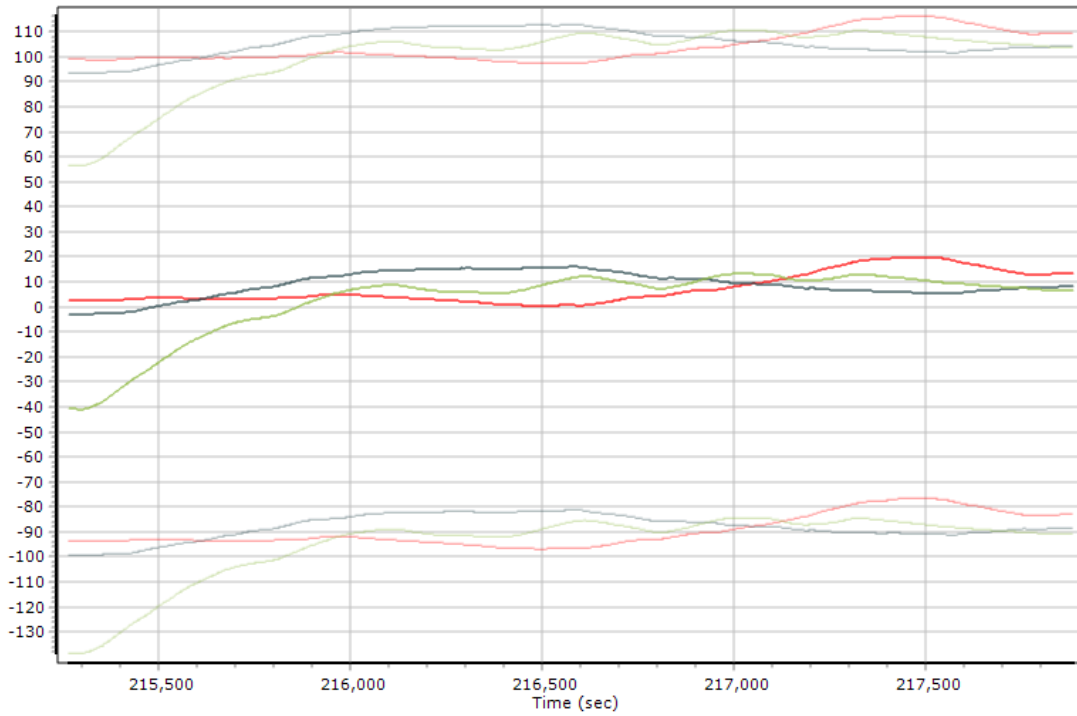


Processing mode

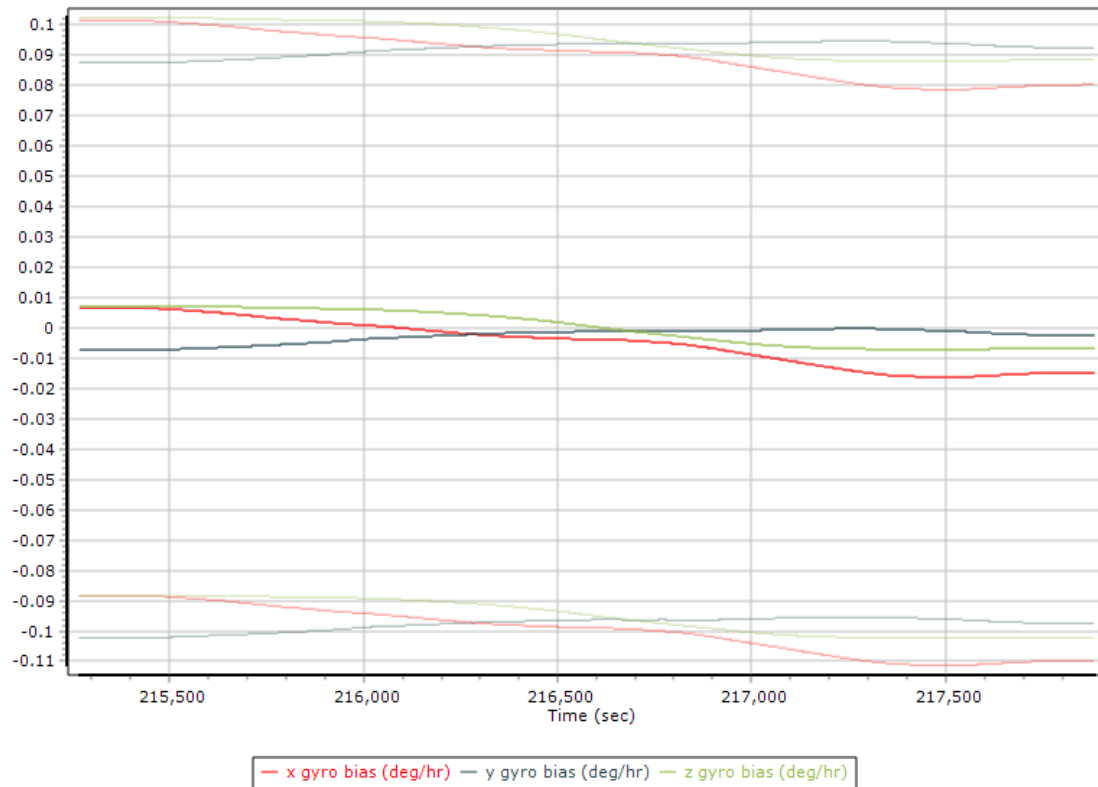
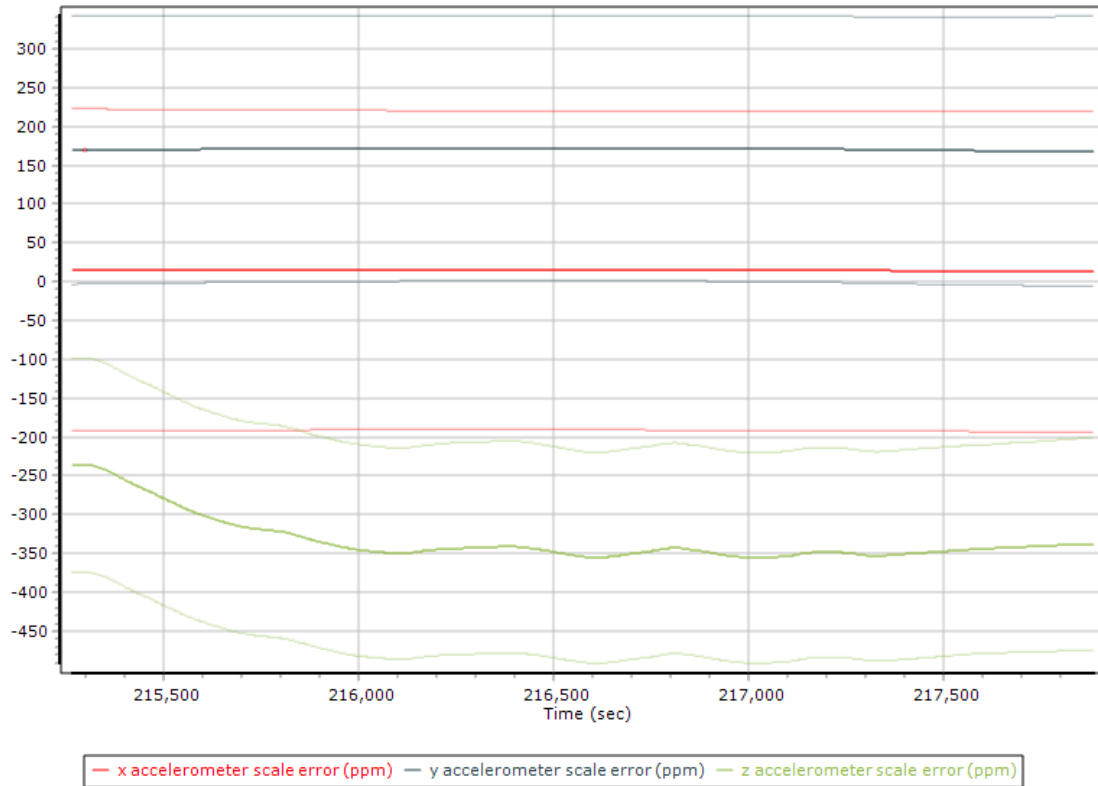


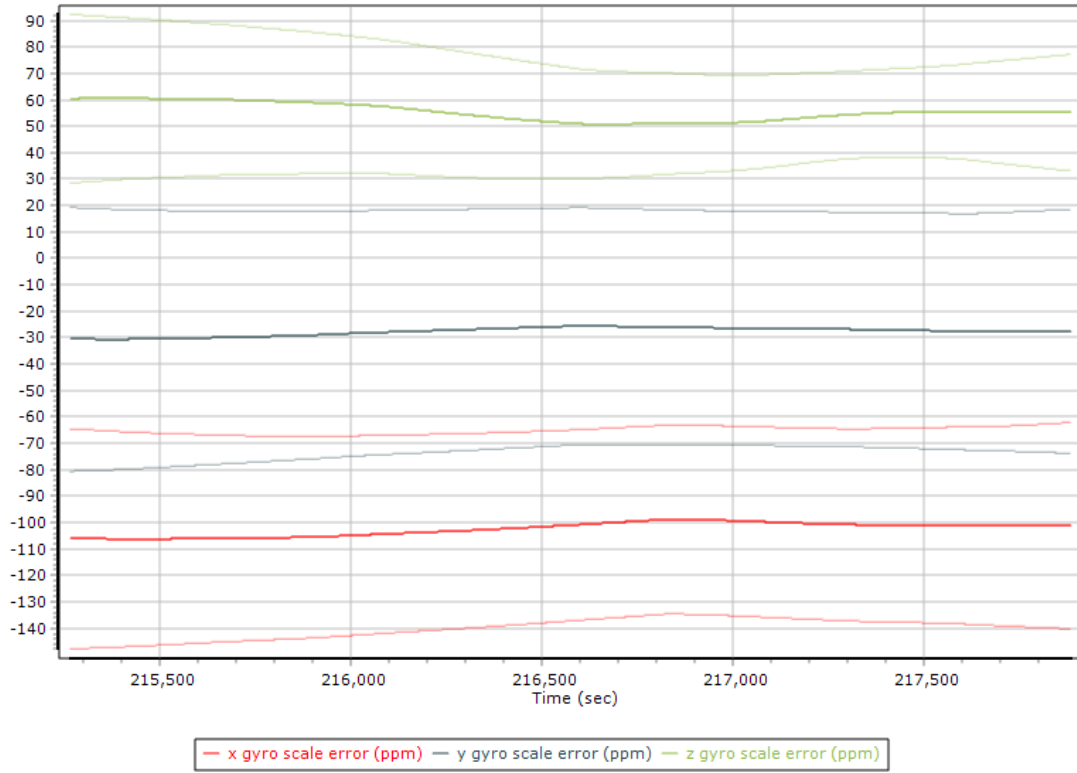
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

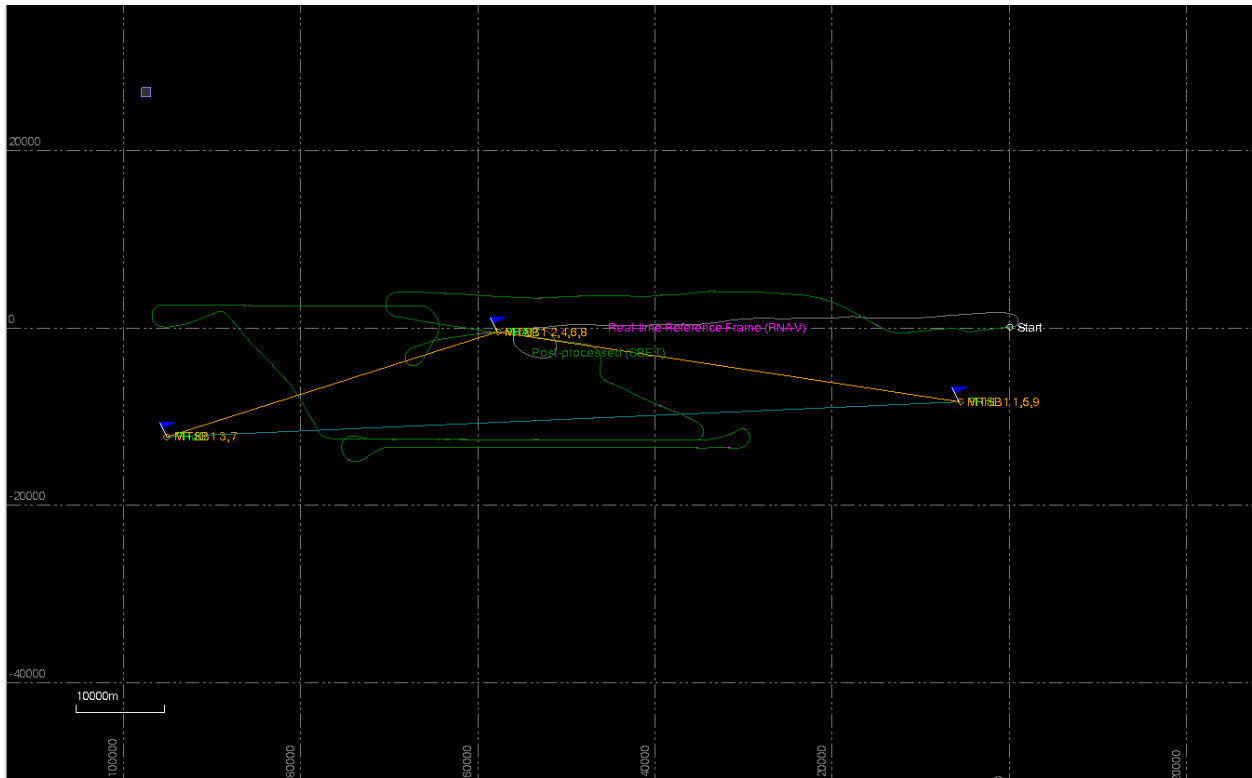


— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)





AZT18130A



Project Settings

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

Stabilized Mount to IMU Lever Arm

X: -0.034 m

Y: -0.010 m

Z: -0.352 m

Stabilized Mount to IMU Mounting Angles

X: 0.000 deg

Y: 0.000 deg

Z: 0.000 deg

Stabilized Mount to Primary GNSS Lever Arm

X: -0.049 m

Y: 0.003 m

Z: -1.230 m

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

Aircraft to Stabilized Mount Mounting Angles

X: 0.000 deg

Y: 0.000 deg

Z: 0.000 deg

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

OK Cancel

Timing

Start: 424282.000

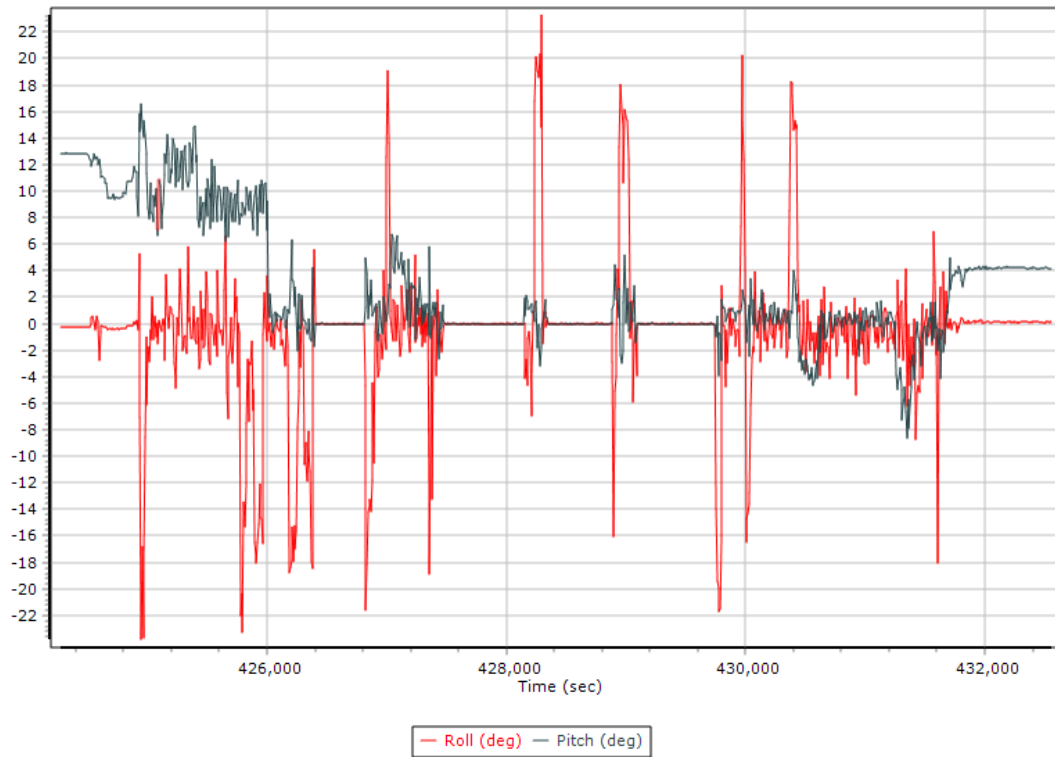
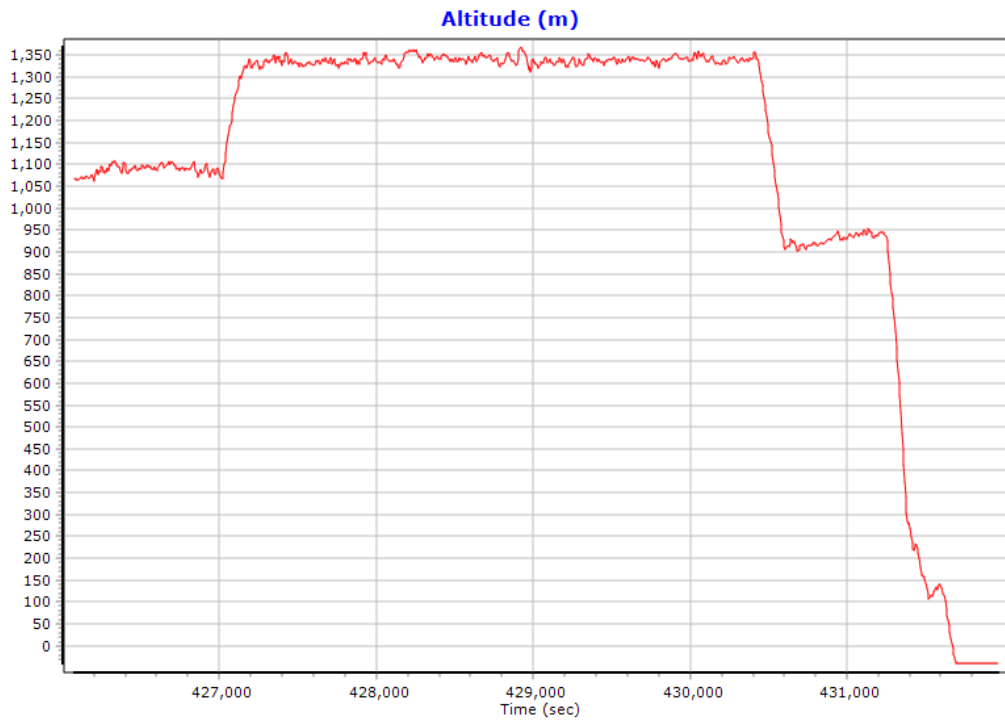
End: 432554.000

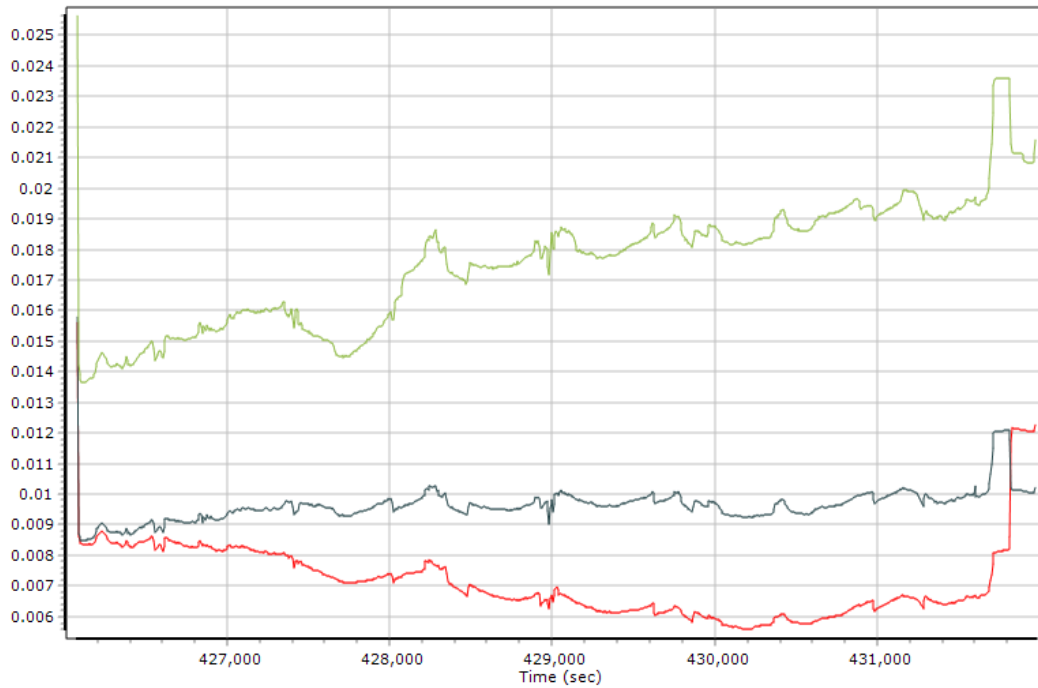
Entire time interval

Seconds of start week

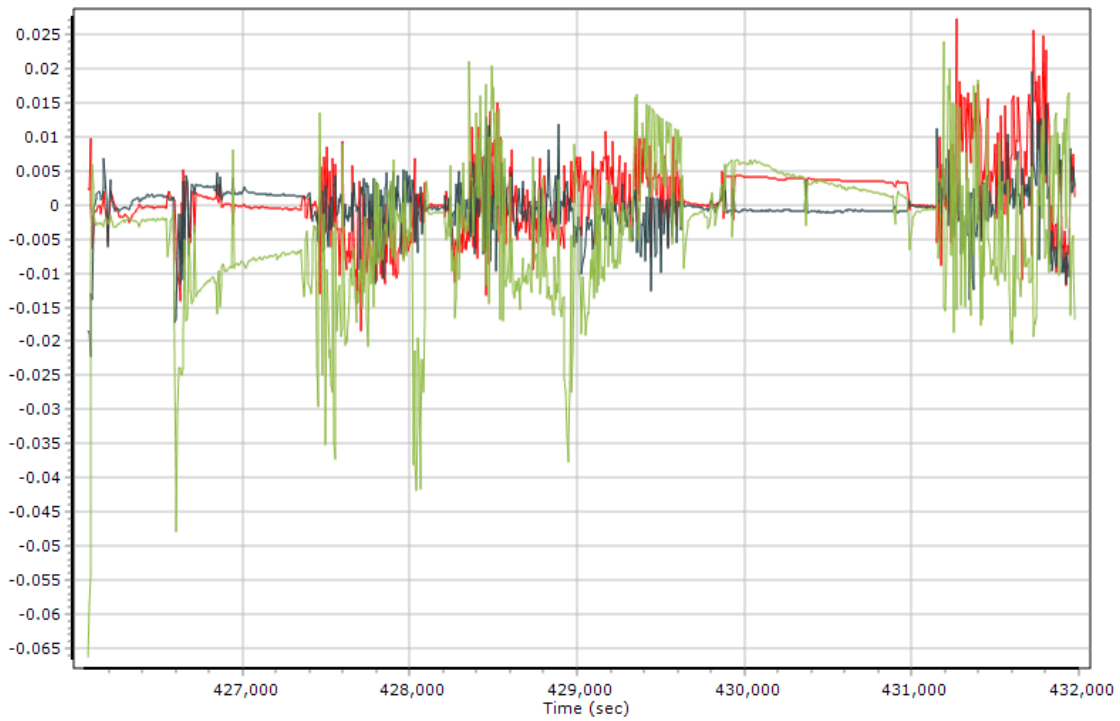
UTC Offset: 18.000

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

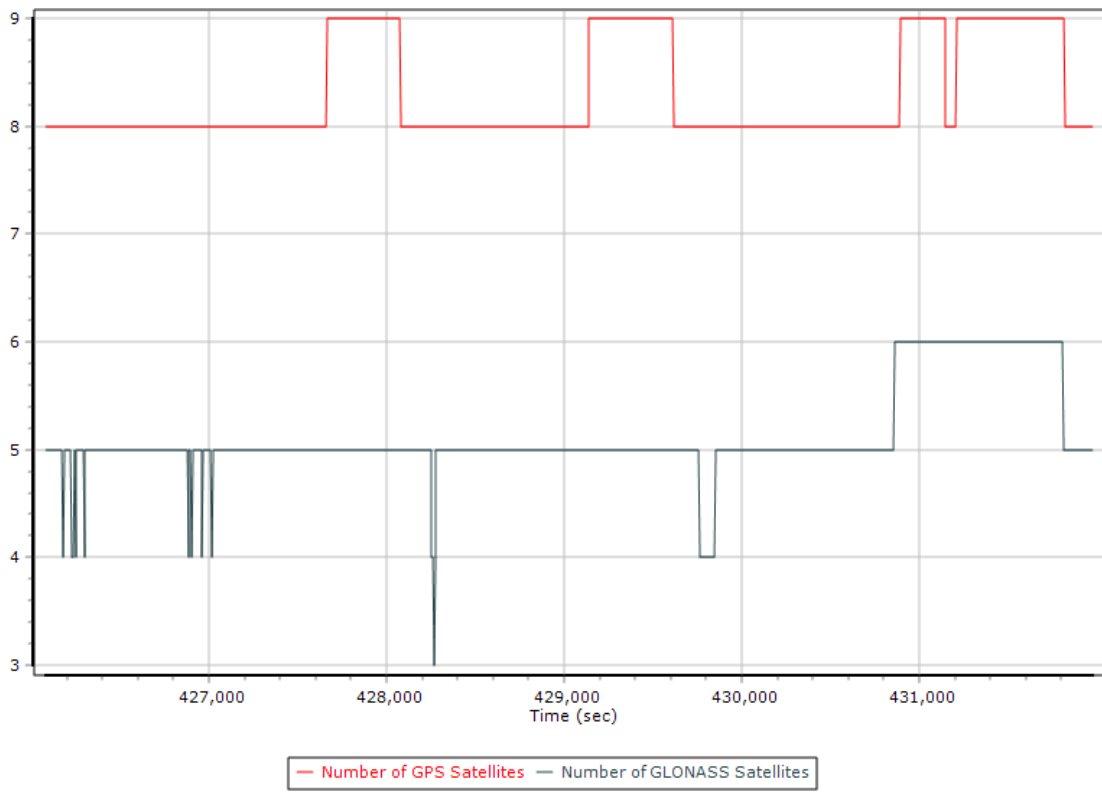




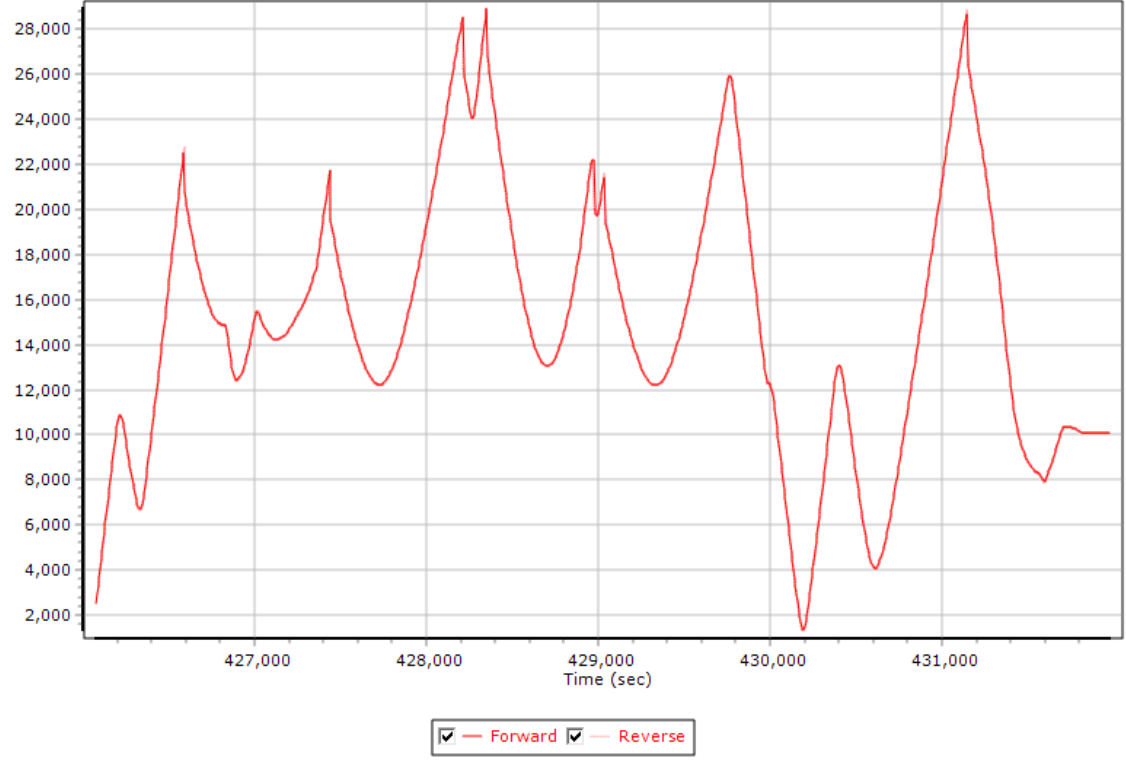
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



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



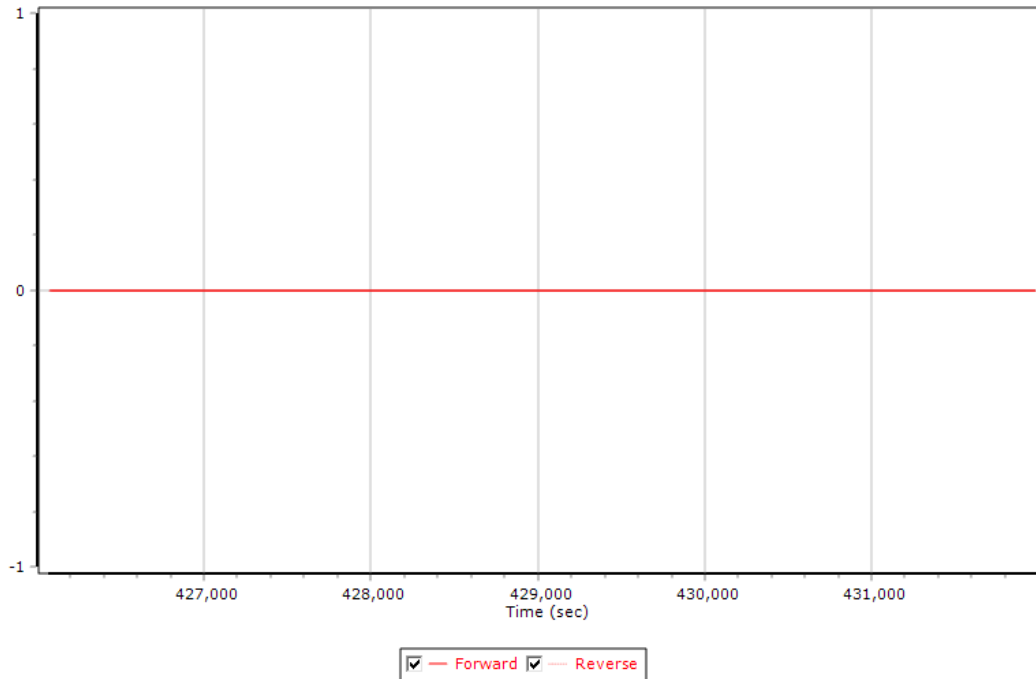
Baseline Length (m)



PDOP

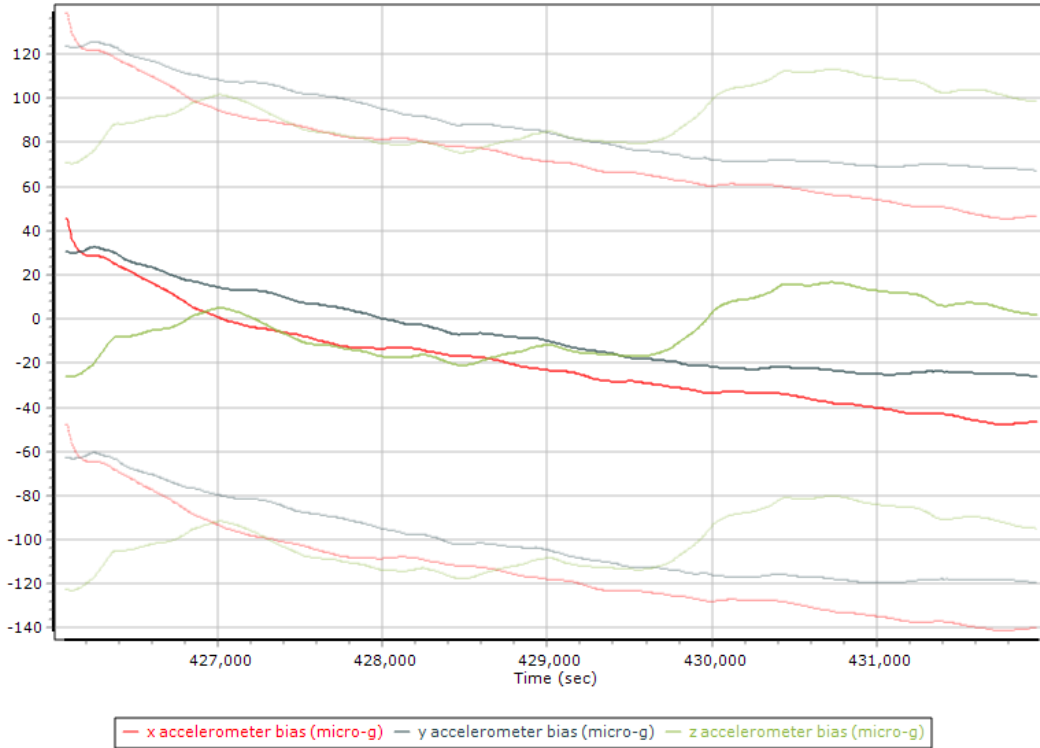


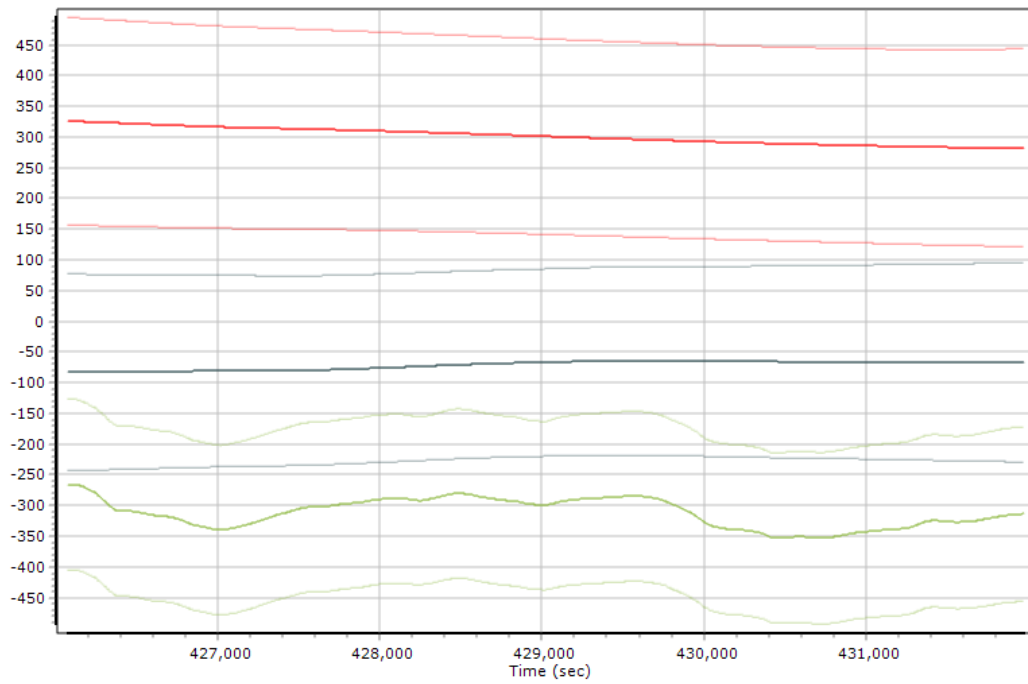
Processing mode



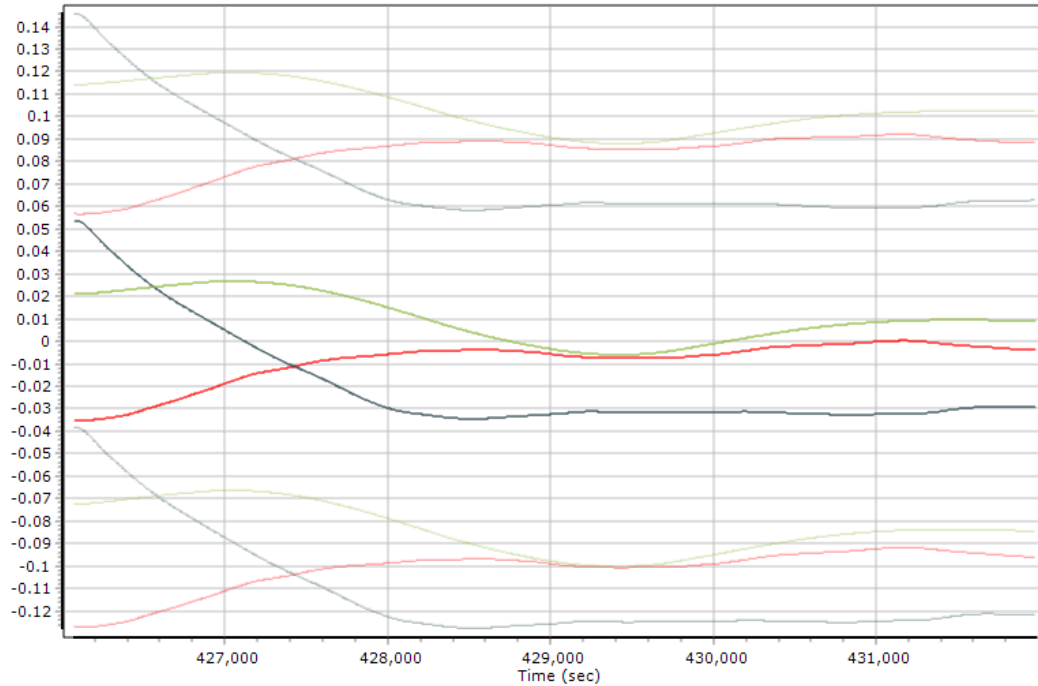
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

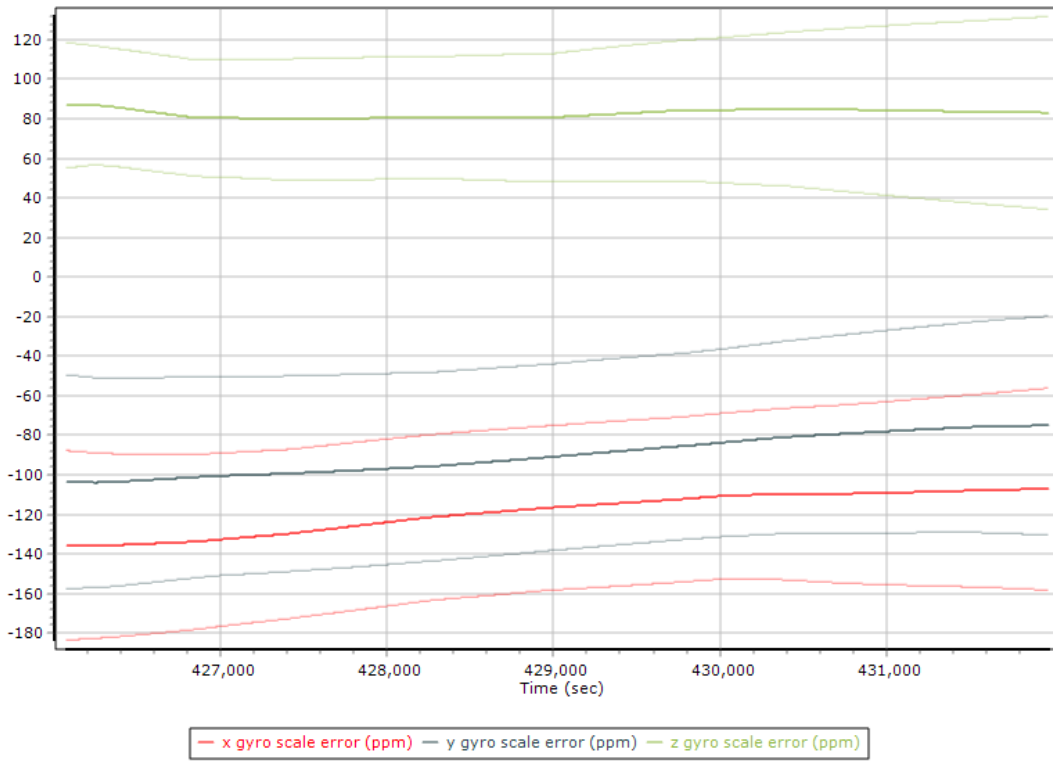




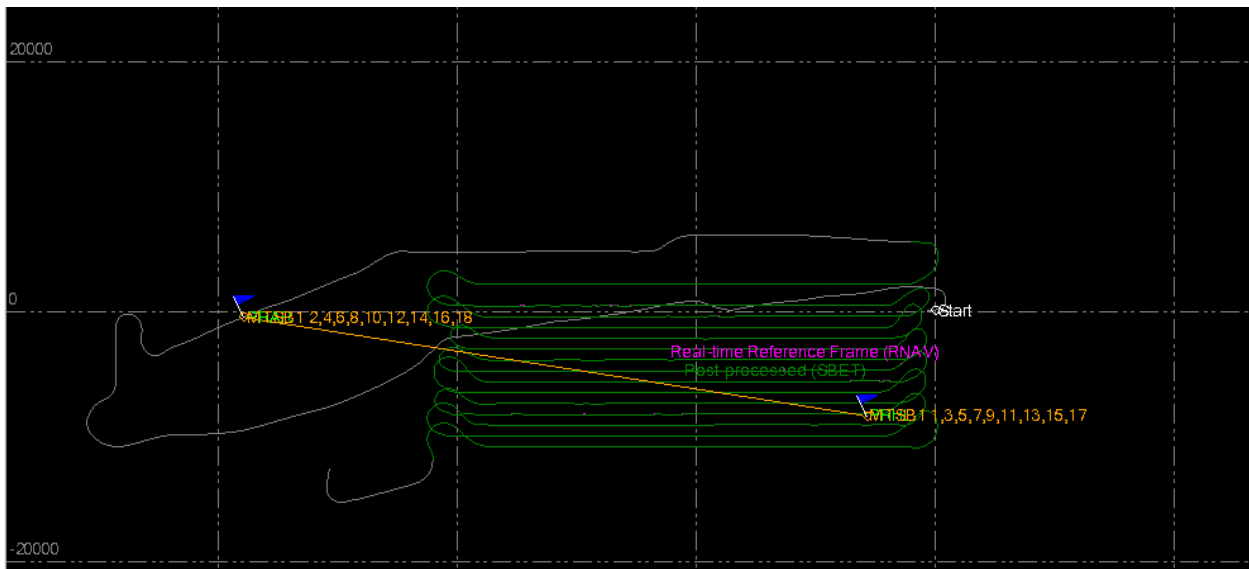
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



AZT18131A



Project Settings

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

Stabilized Mount to IMU Lever Arm

X: -0.034 m

Y: -0.010 m

Z: -0.352 m

Stabilized Mount to IMU Mounting Angles

X: 0.000 deg

Y: 0.000 deg

Z: 0.000 deg

Stabilized Mount to Primary GNSS Lever Arm

X: -0.049 m

Y: 0.003 m

Z: -1.230 m

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

Aircraft to Stabilized Mount Mounting Angles

X: 0.000 deg

Y: 0.000 deg

Z: 0.000 deg

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

OK Cancel

Timing

Start: 515758.816

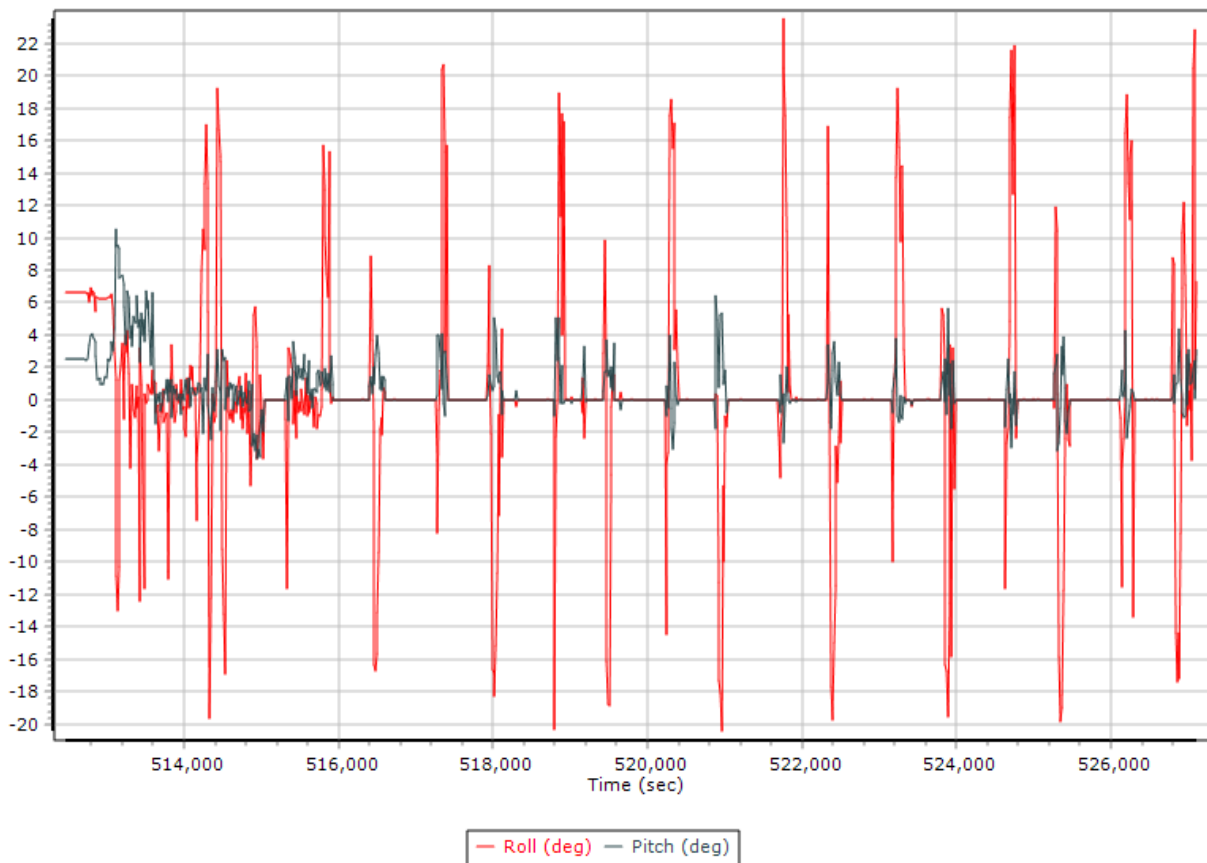
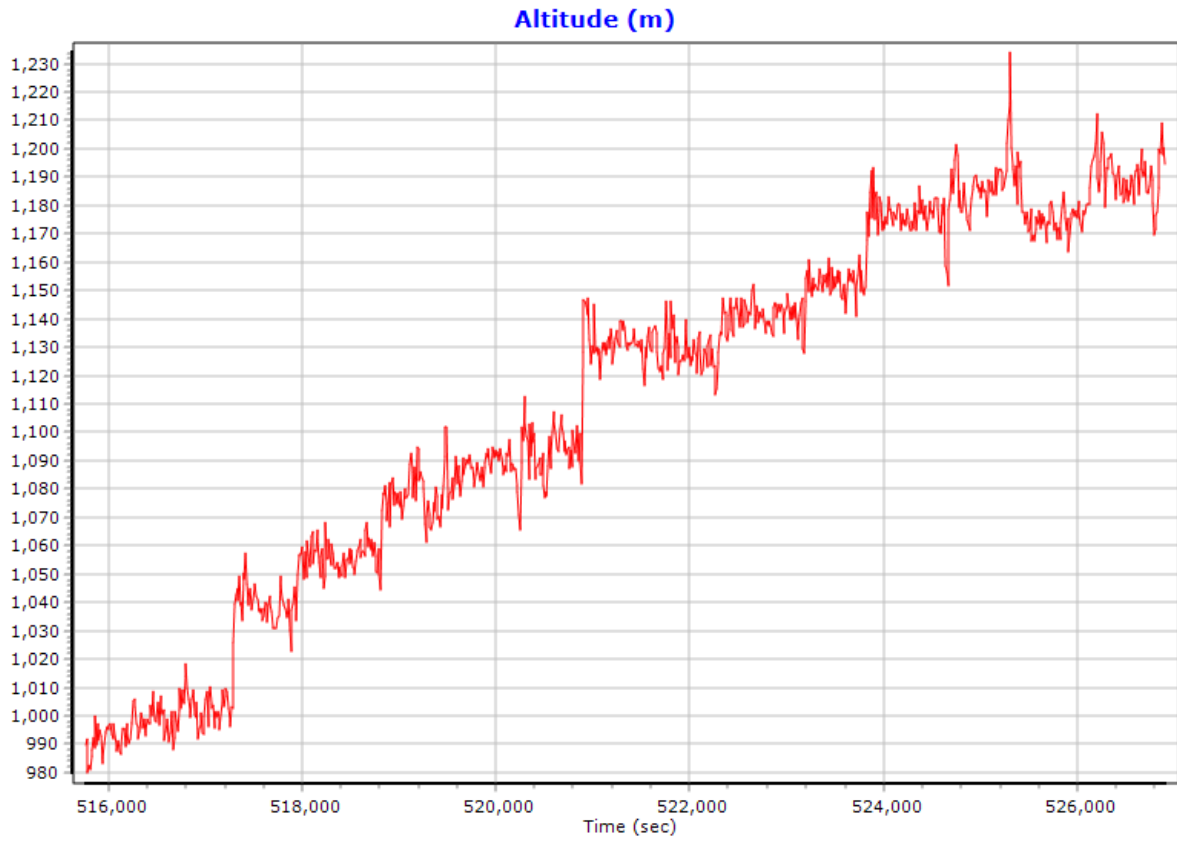
End: 526923.412

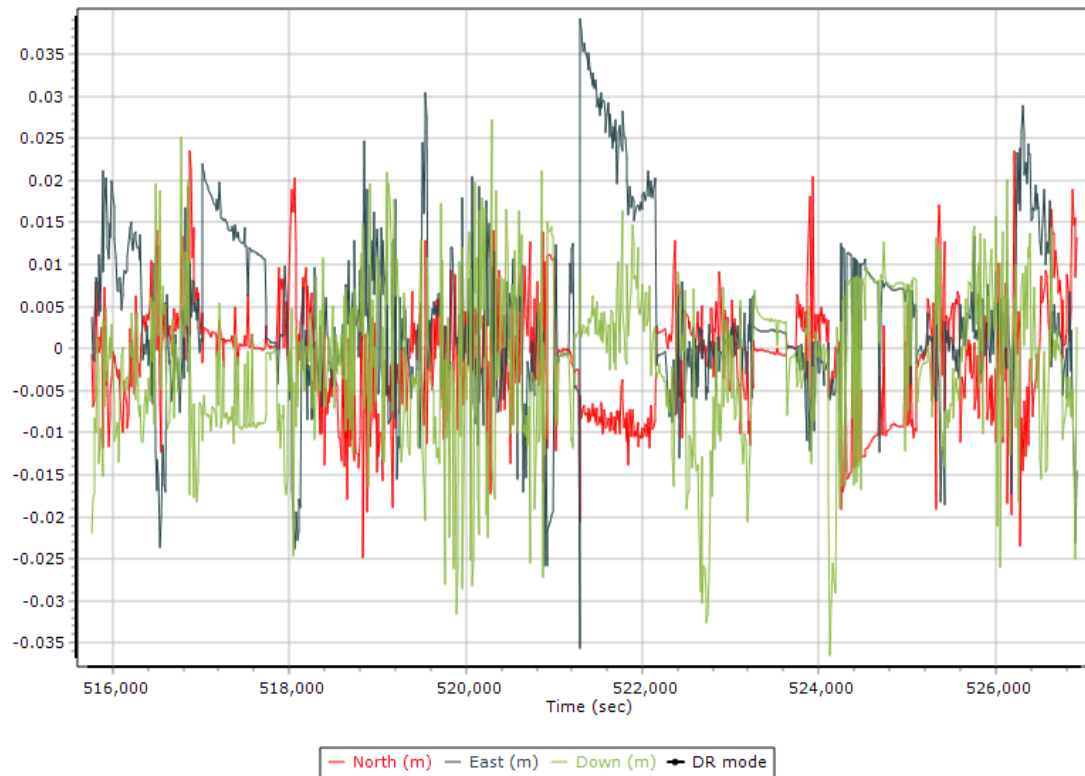
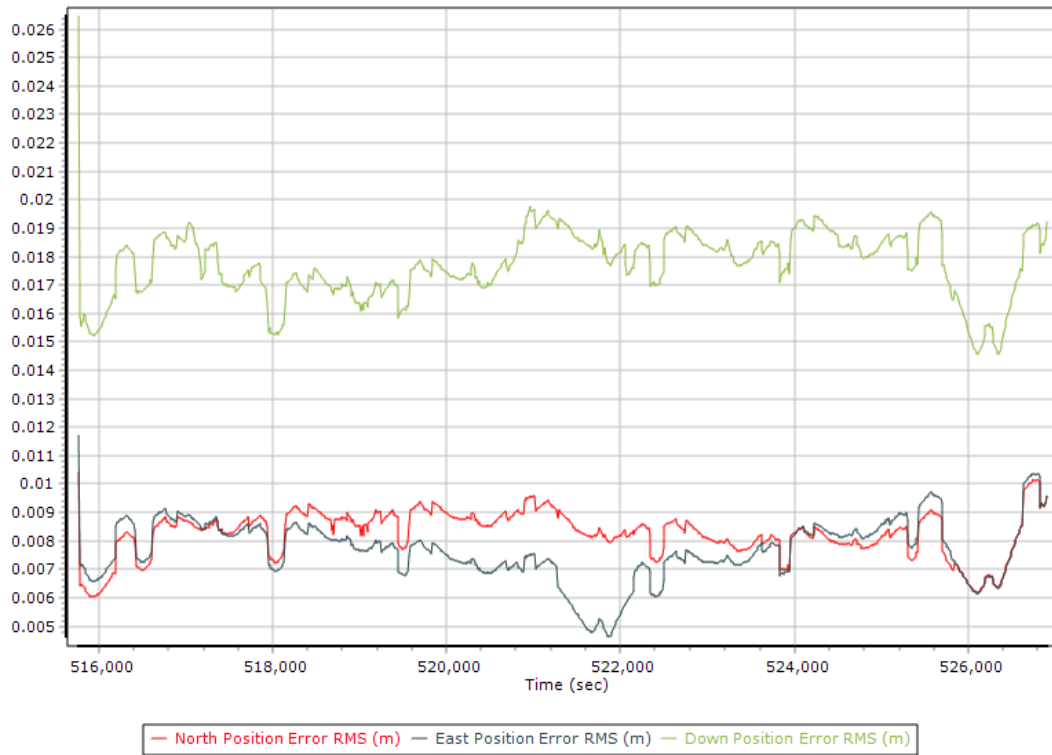
Entire time interval

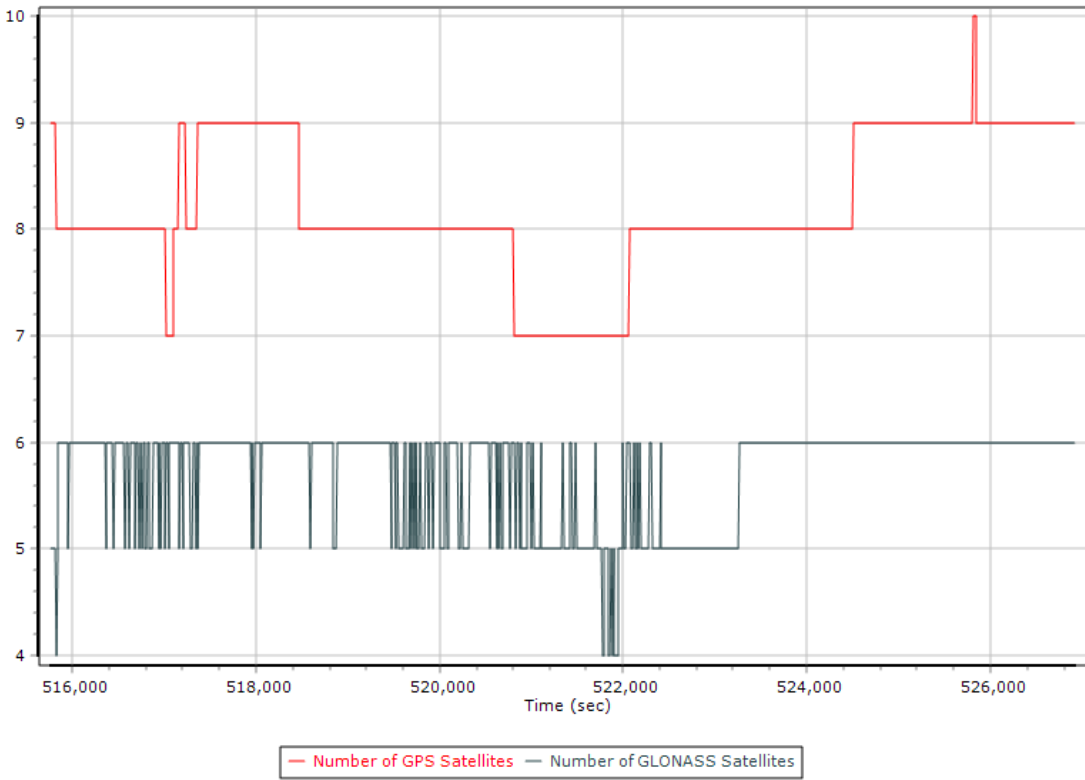
Seconds of start week

UTC Offset: 18.000

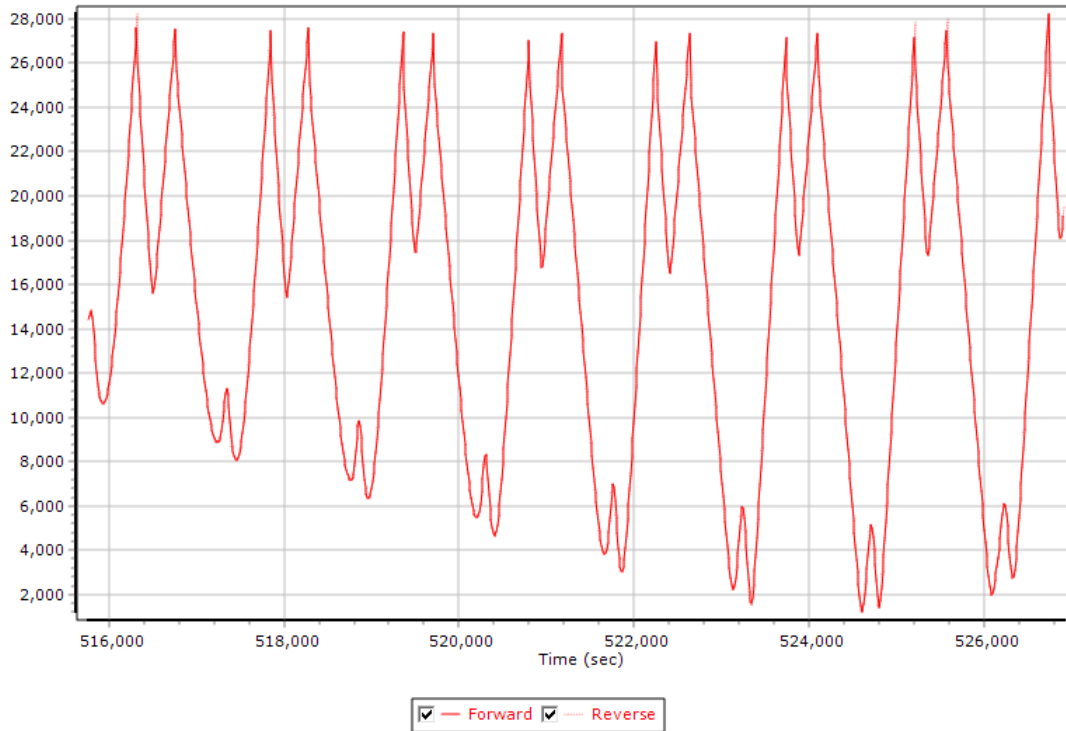
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

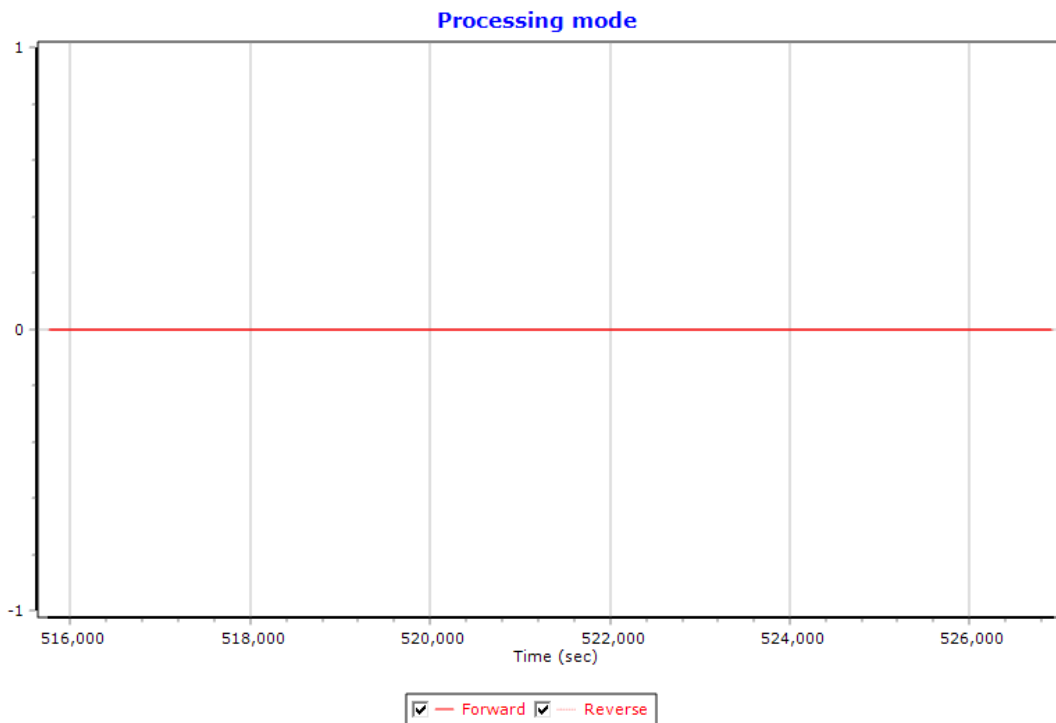
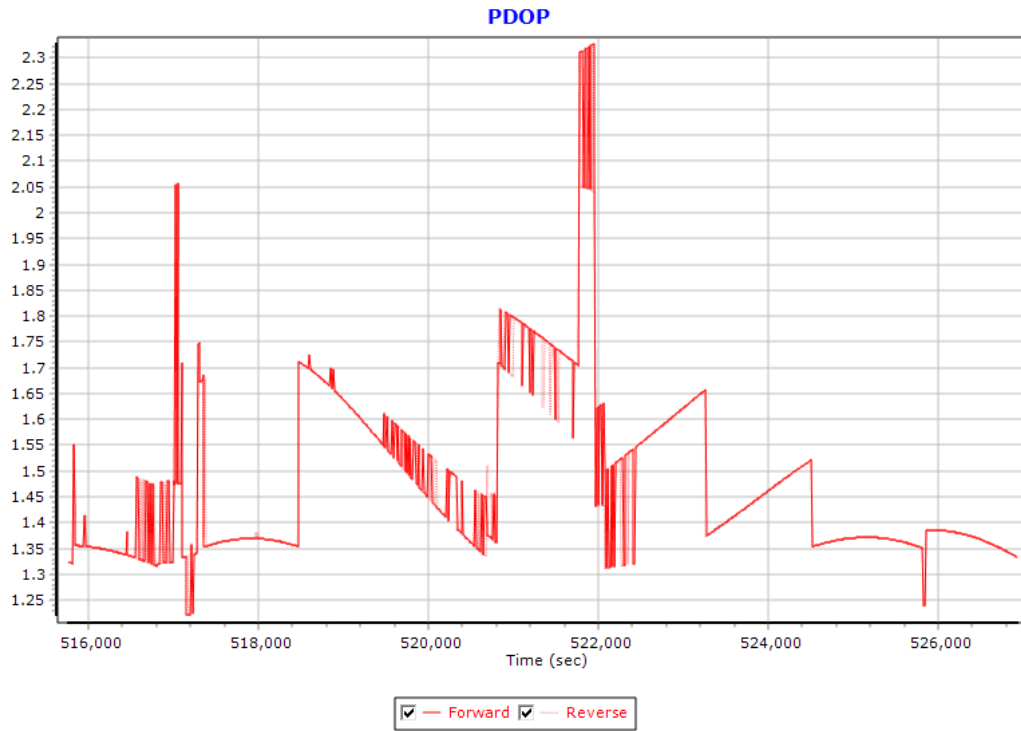






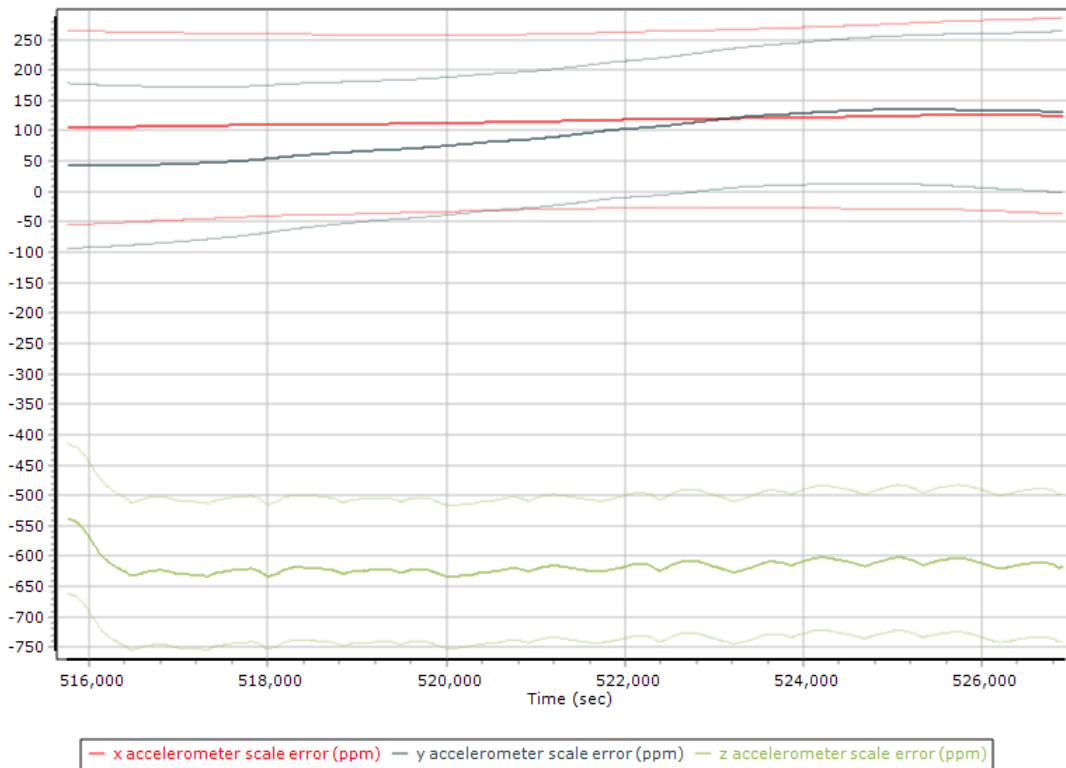
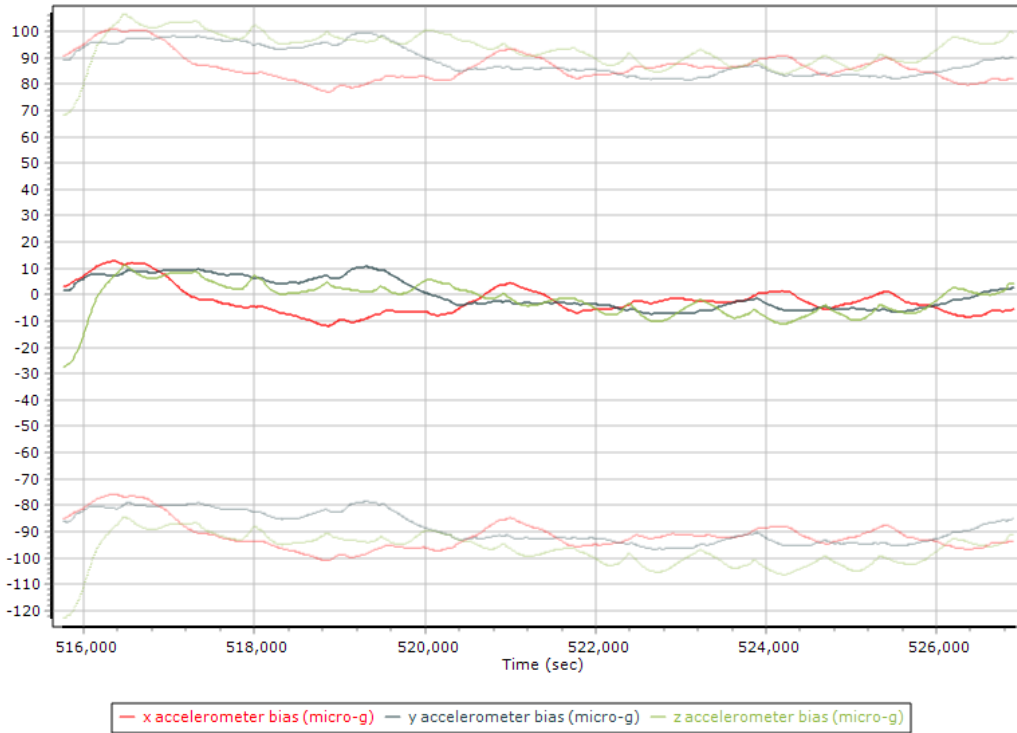
Baseline Length (m)

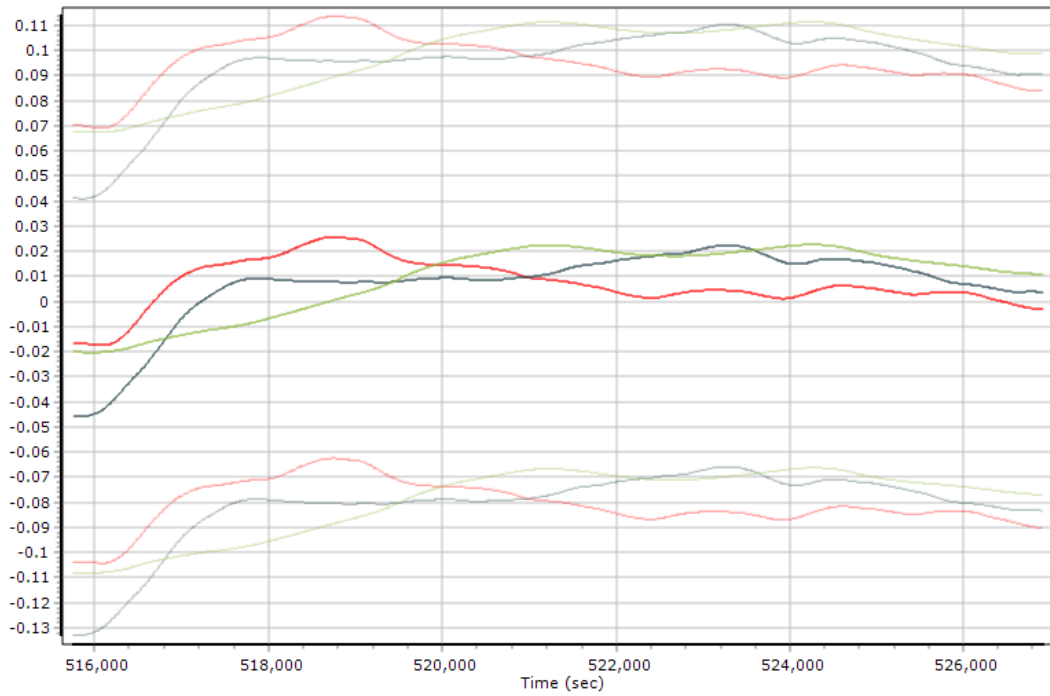




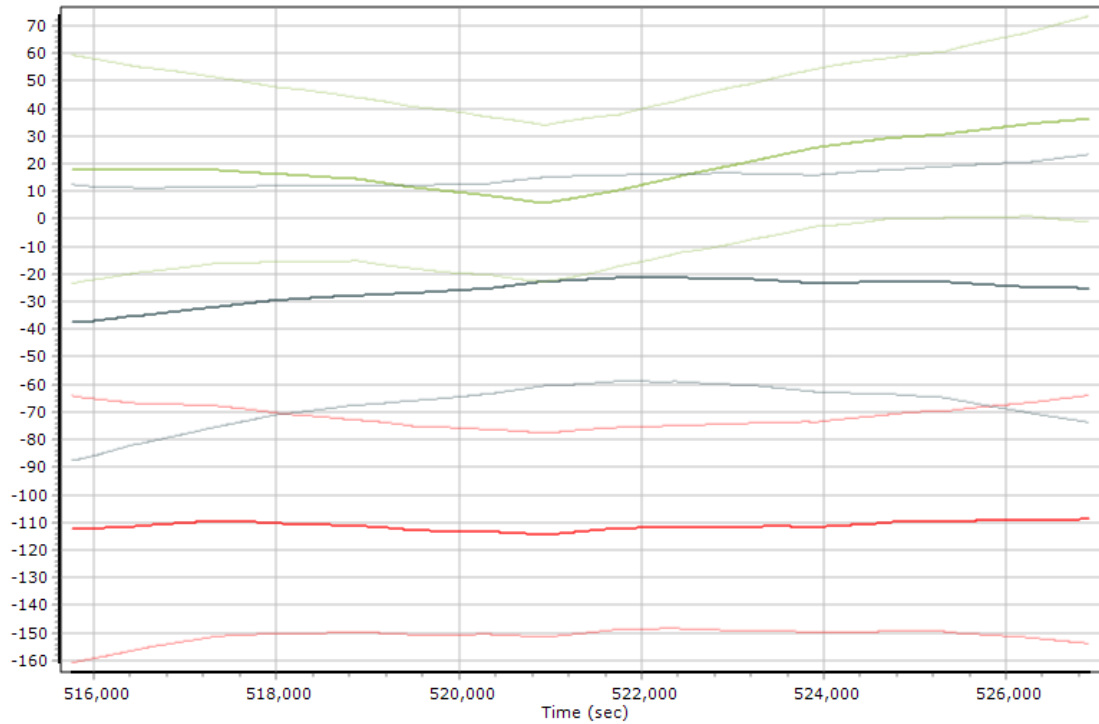
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors



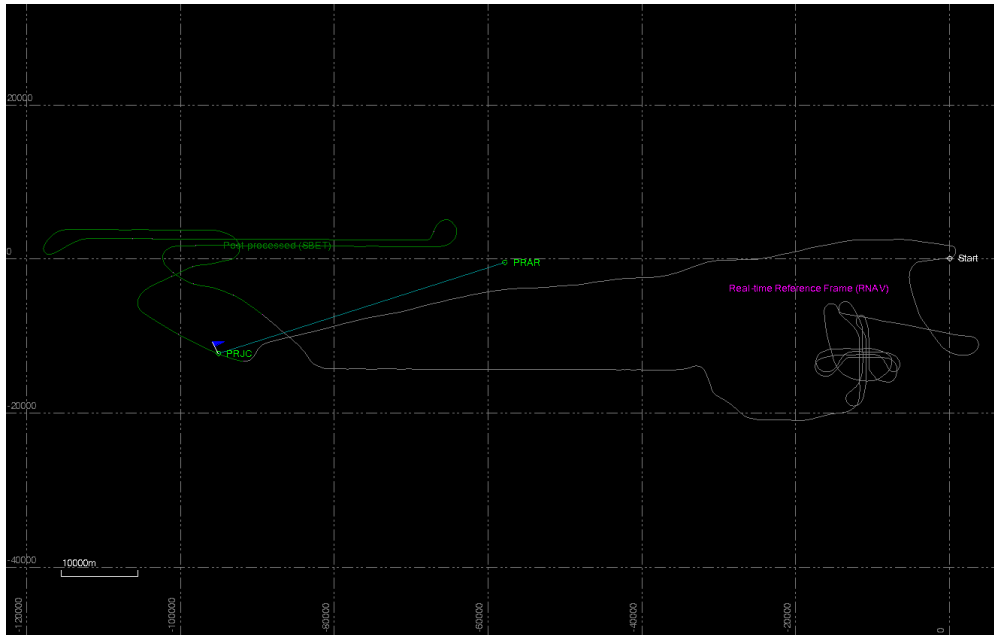


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



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

AZT18132A



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.

Timing

Start

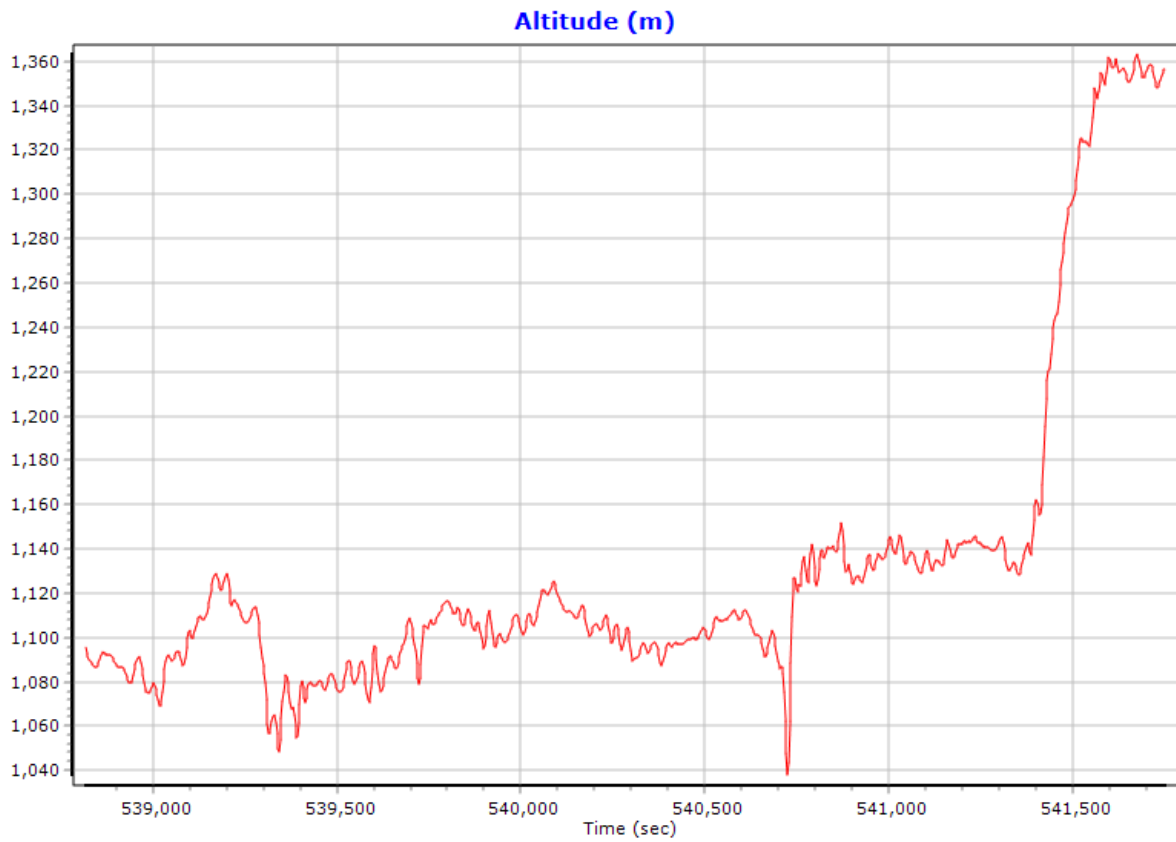
End

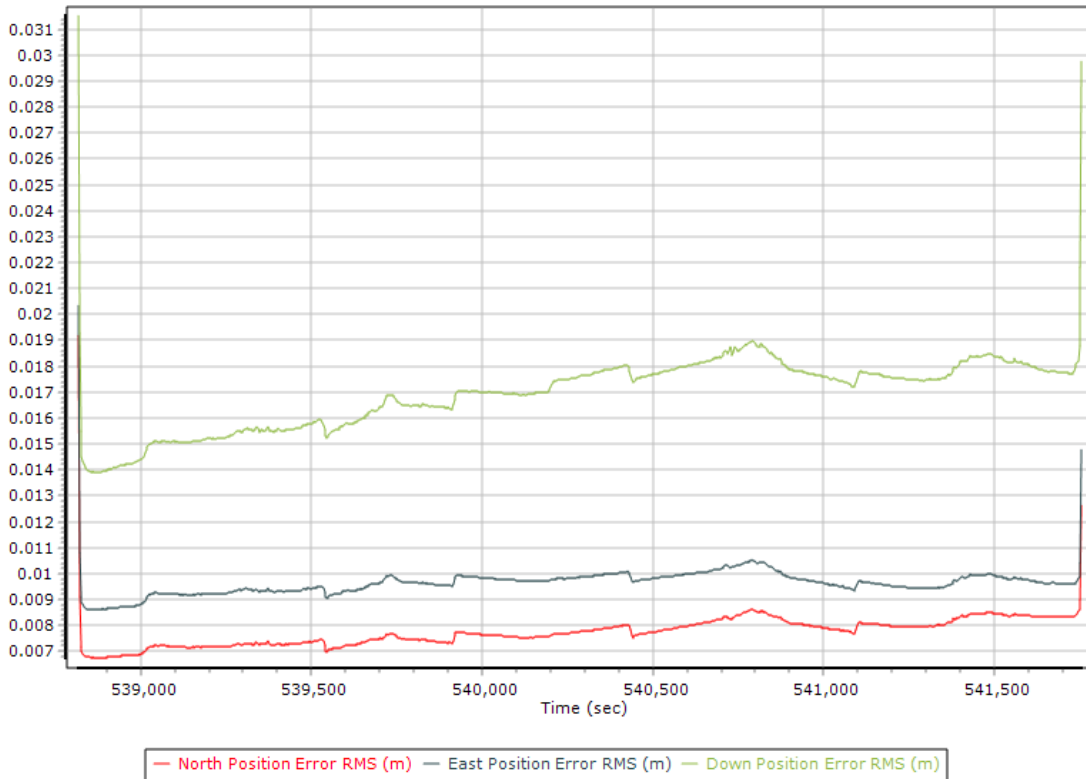
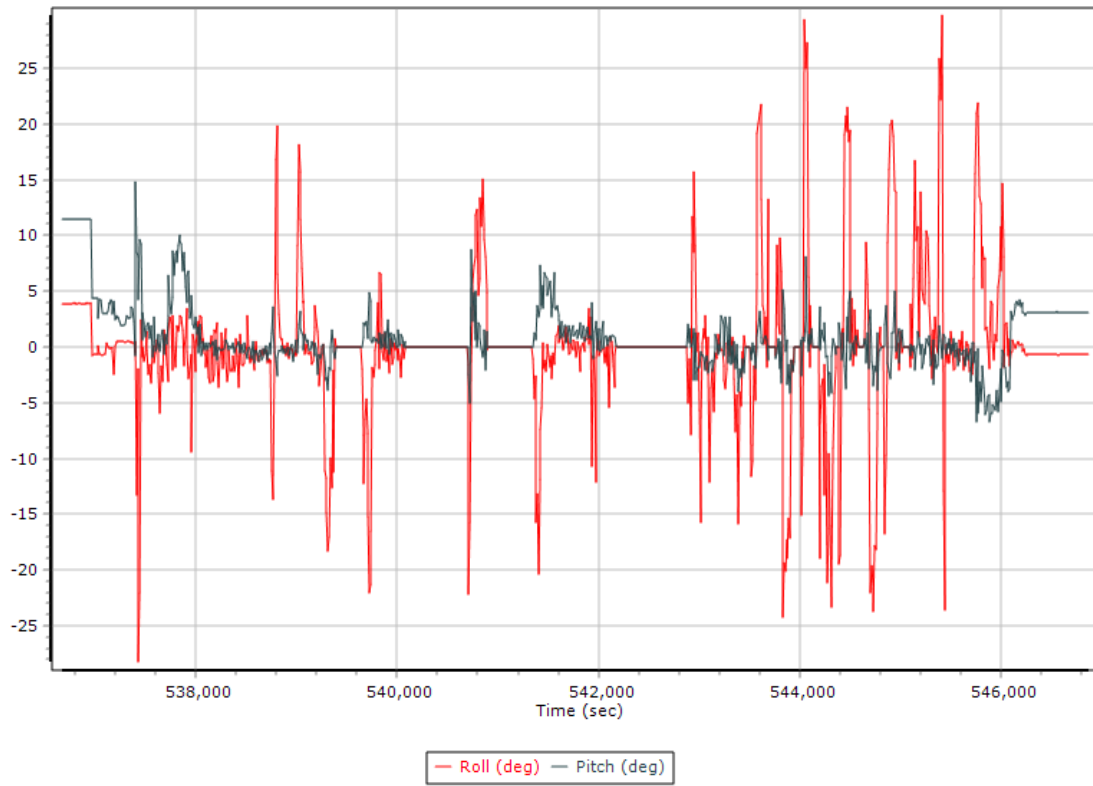
Entire time interval

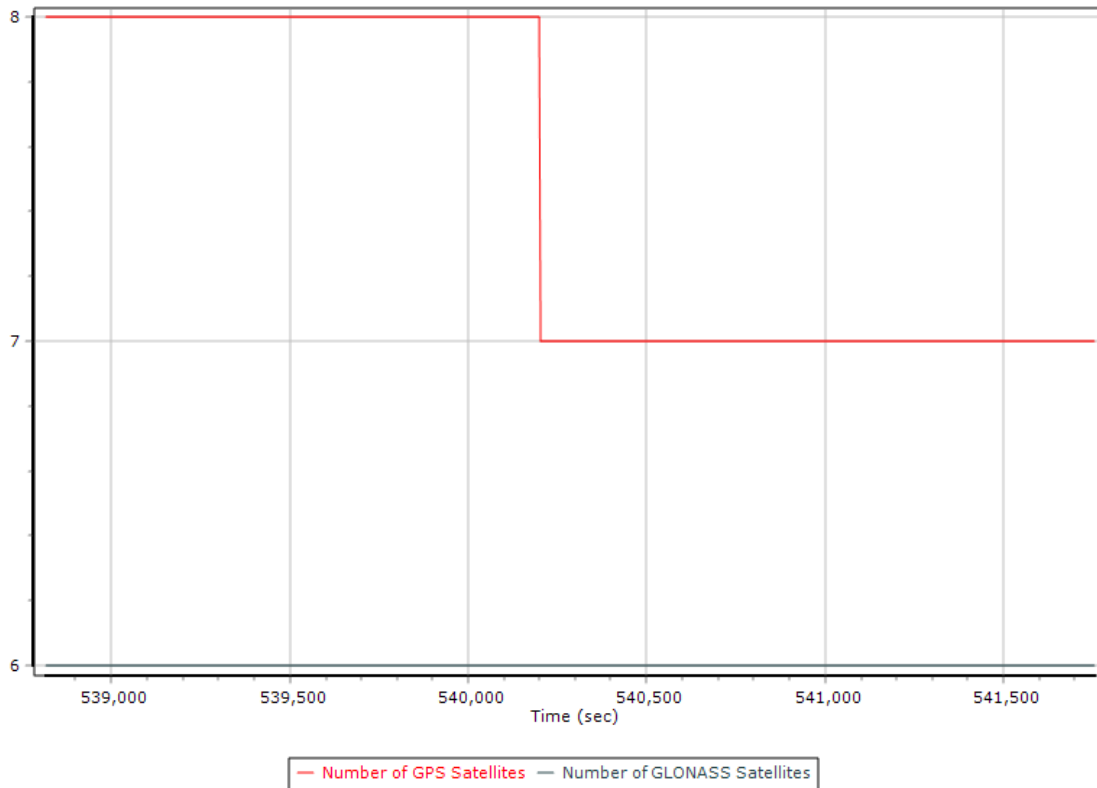
Seconds of start week

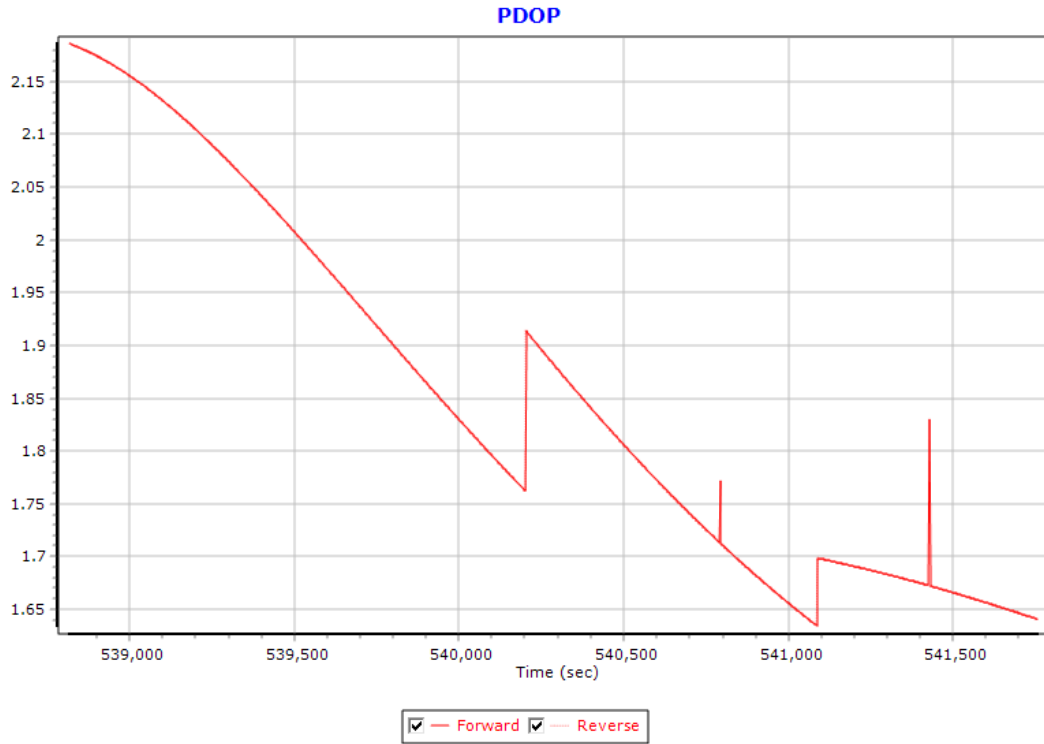
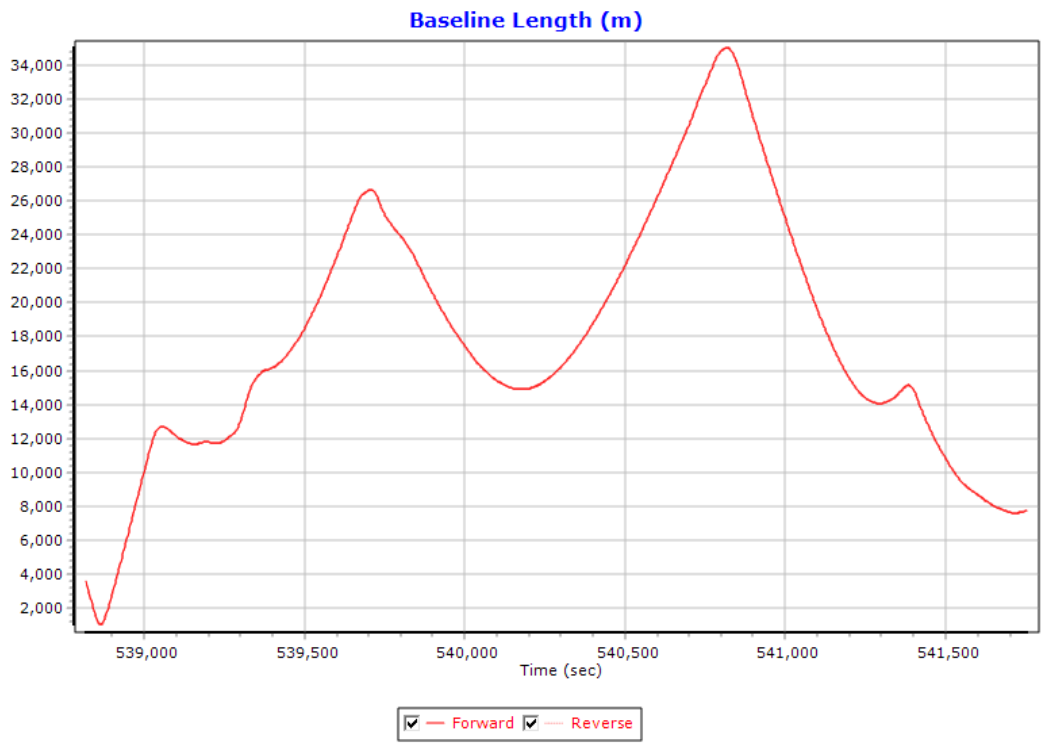
UTC Offset

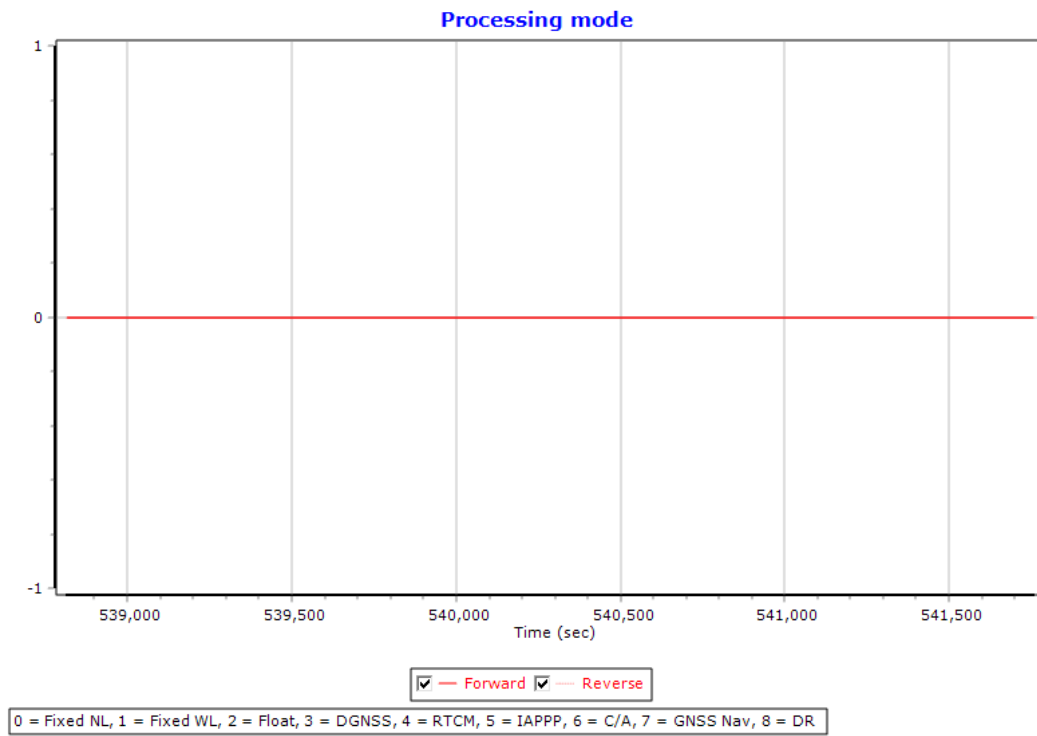
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



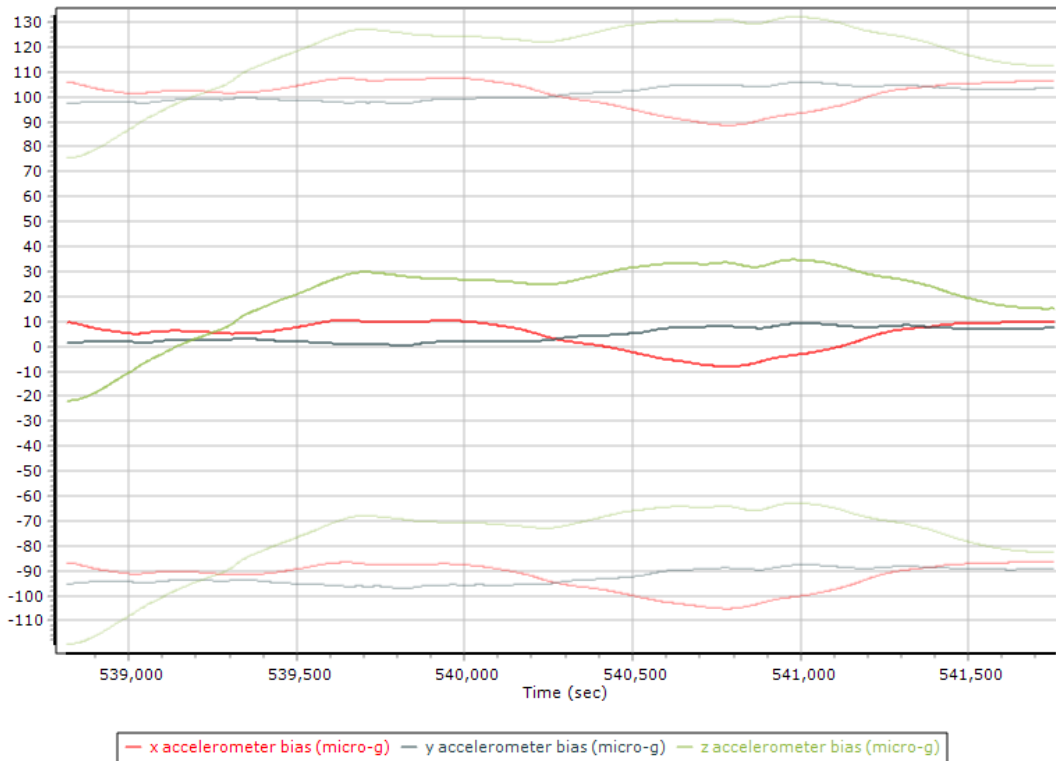


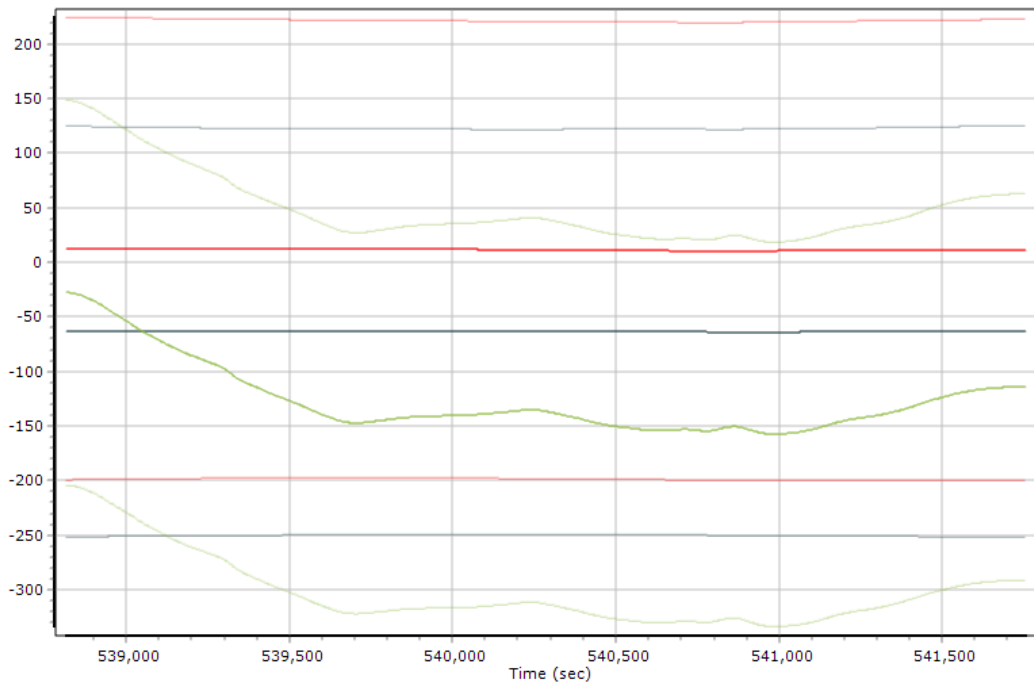




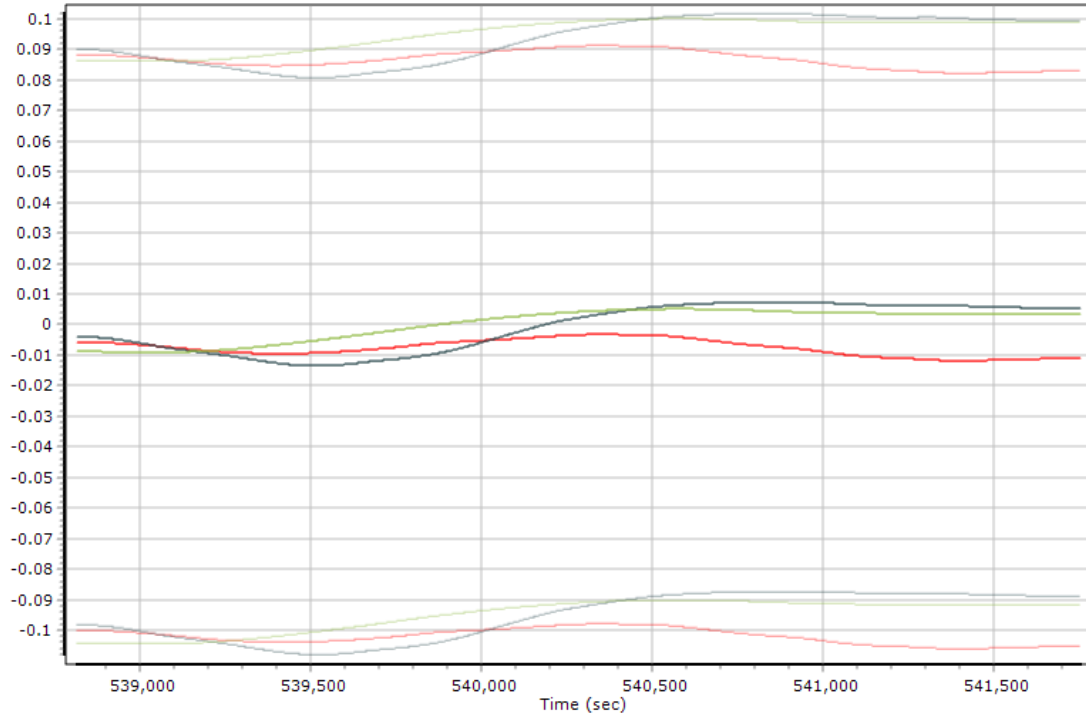


Sensor Errors

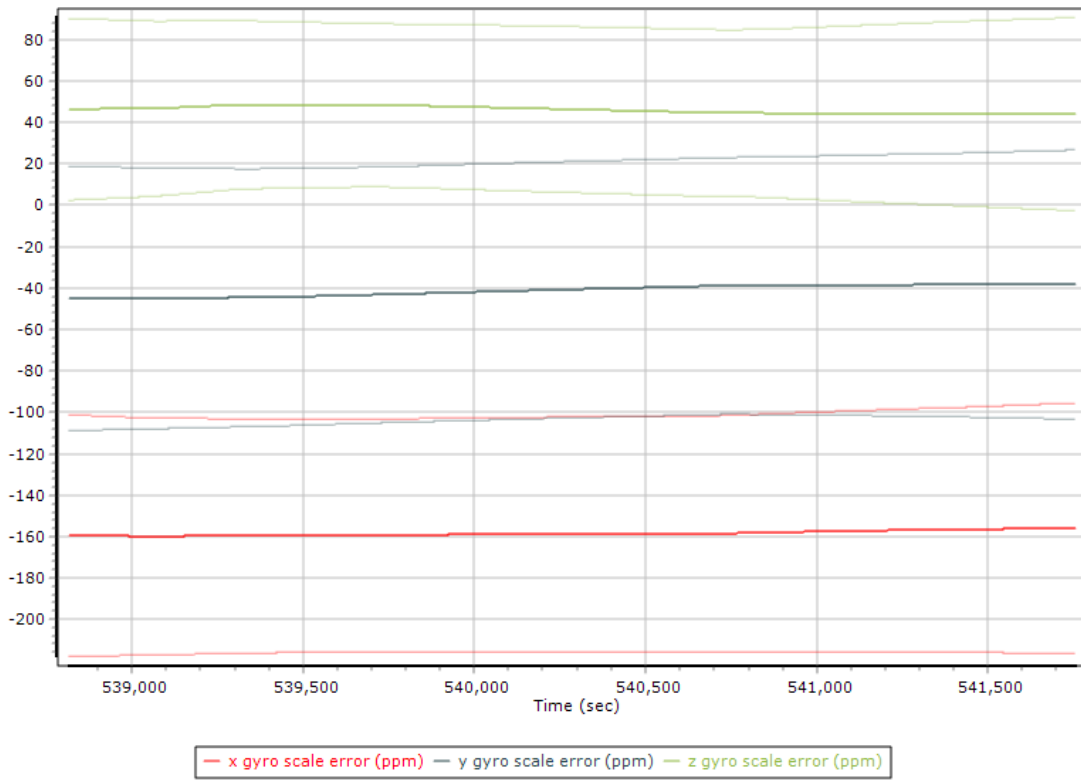




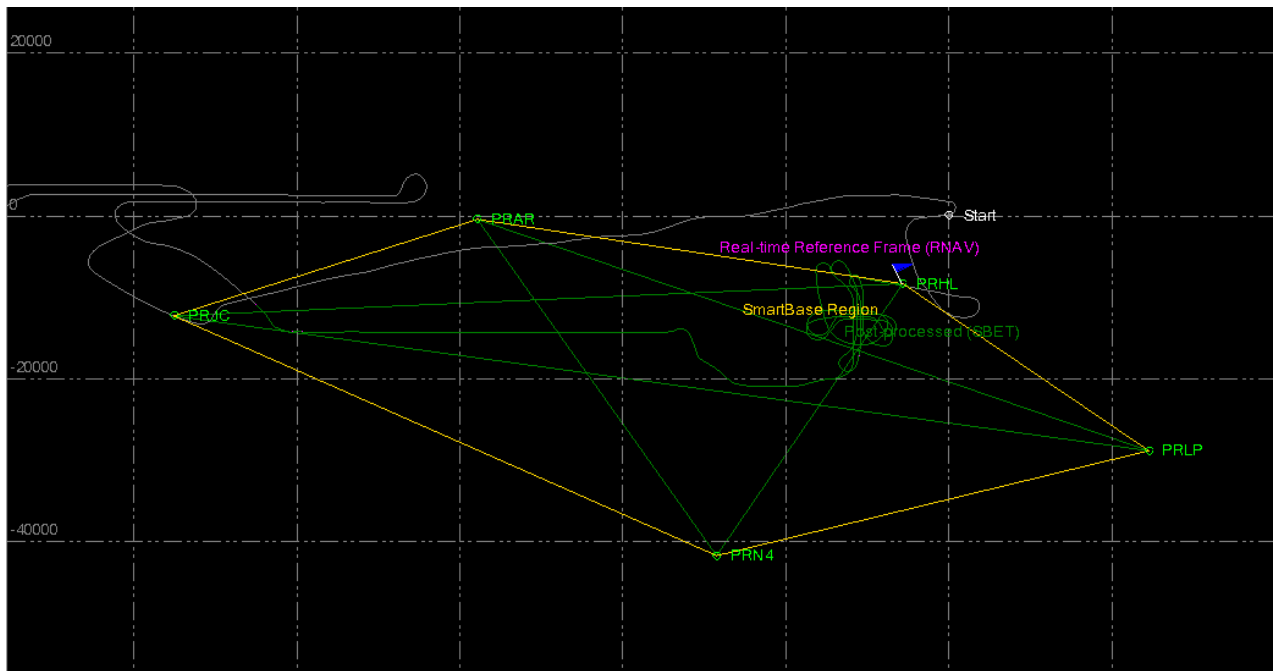
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



AZT18132A2



Project Settings

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

Stabilized Mount to IMU Lever Arm

X: -0.034 m

Y: -0.010 m

Z: -0.352 m

Stabilized Mount to IMU Mounting Angles

X: 0.000 deg

Y: 0.000 deg

Z: 0.000 deg

Stabilized Mount to Primary GNSS Lever Arm

X: -0.049 m

Y: 0.003 m

Z: -1.230 m

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

Aircraft to Stabilized Mount Mounting Angles

X: 0.000 deg

Y: 0.000 deg

Z: 0.000 deg

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

OK Cancel

Timing

Start: 541867.120

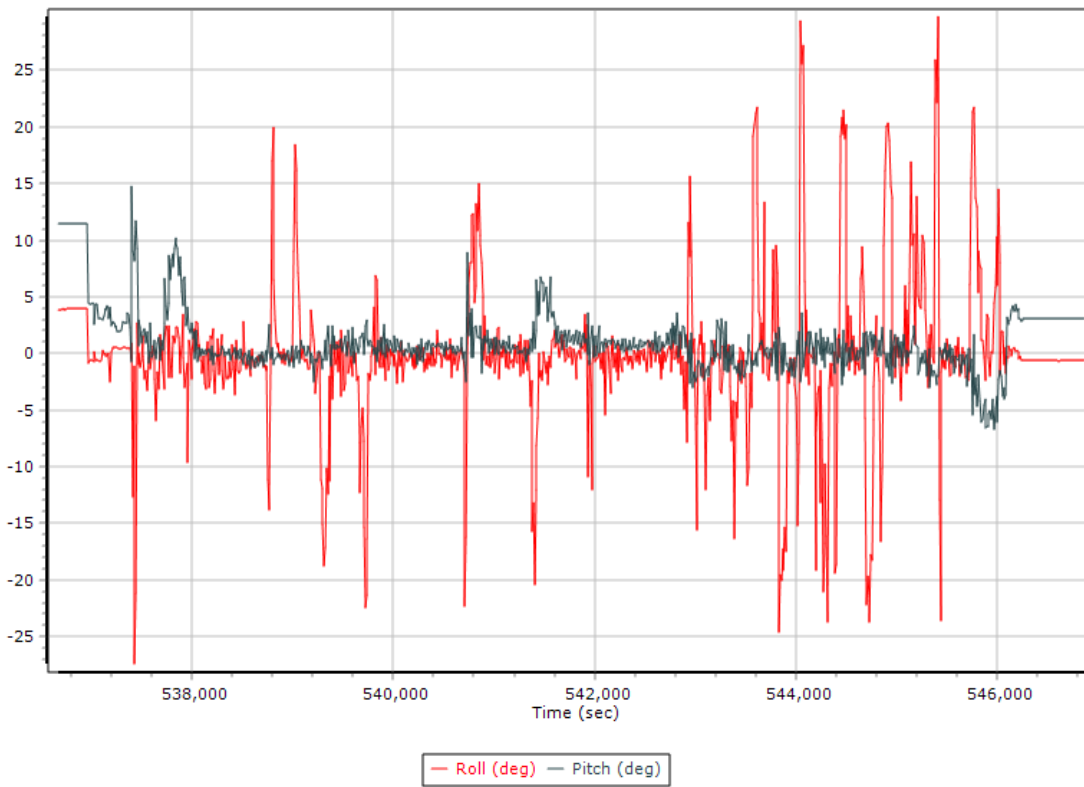
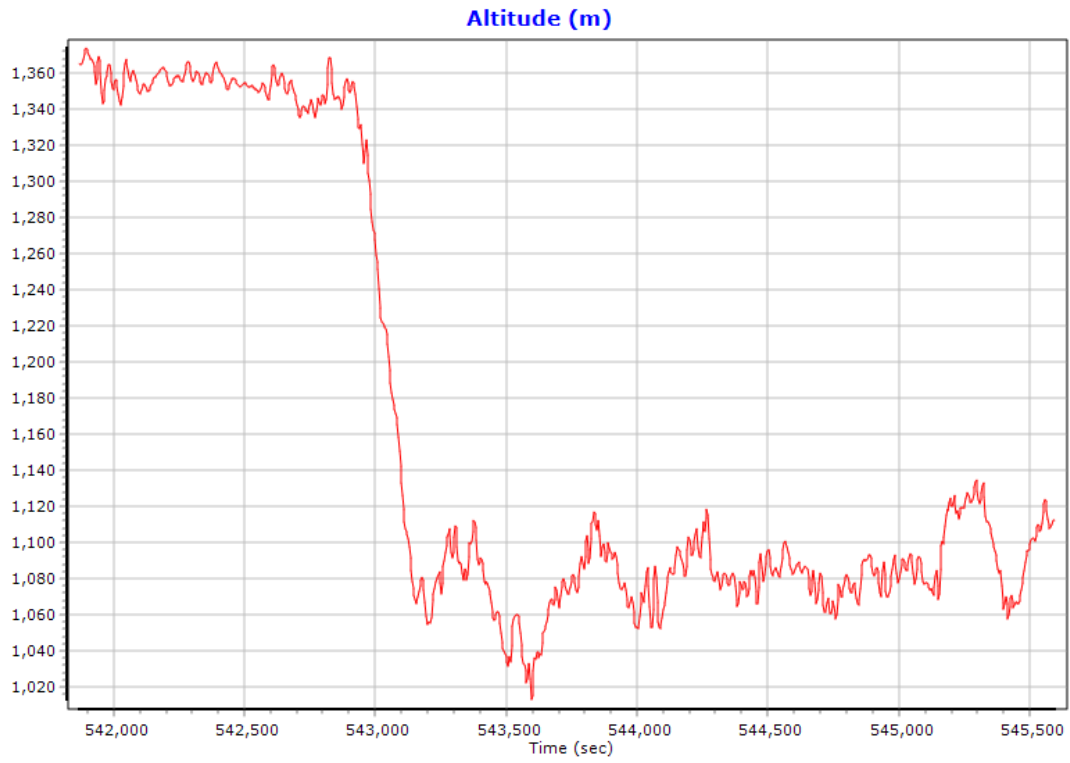
End: 545599.986

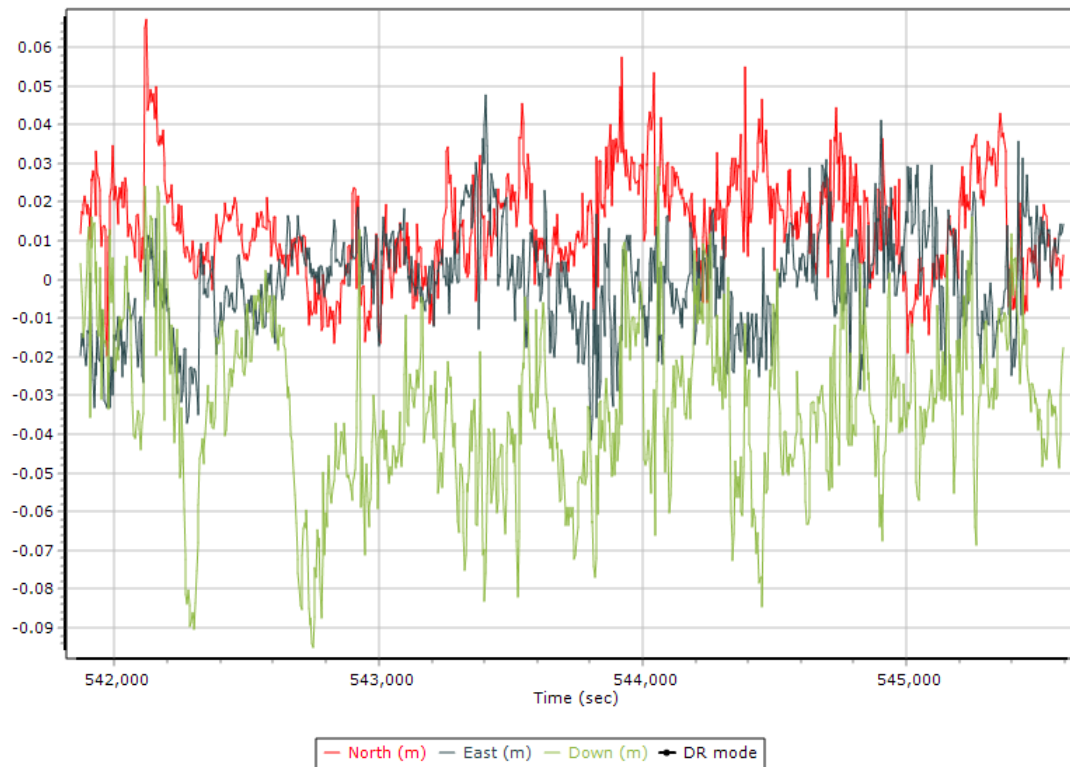
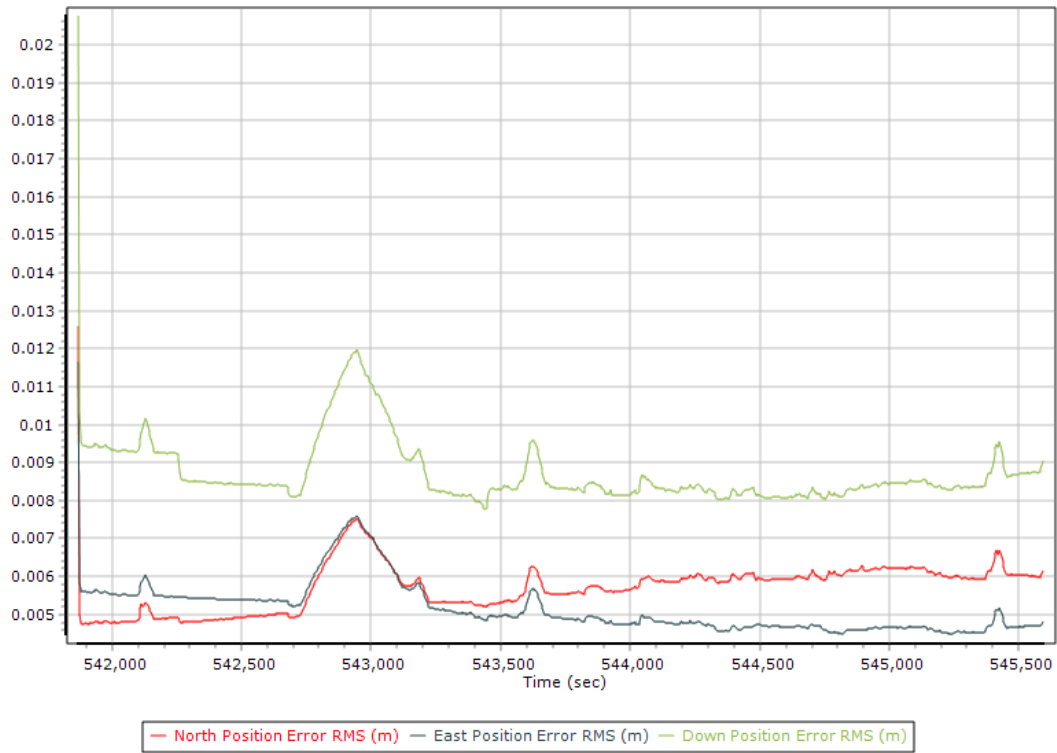
Entire time interval

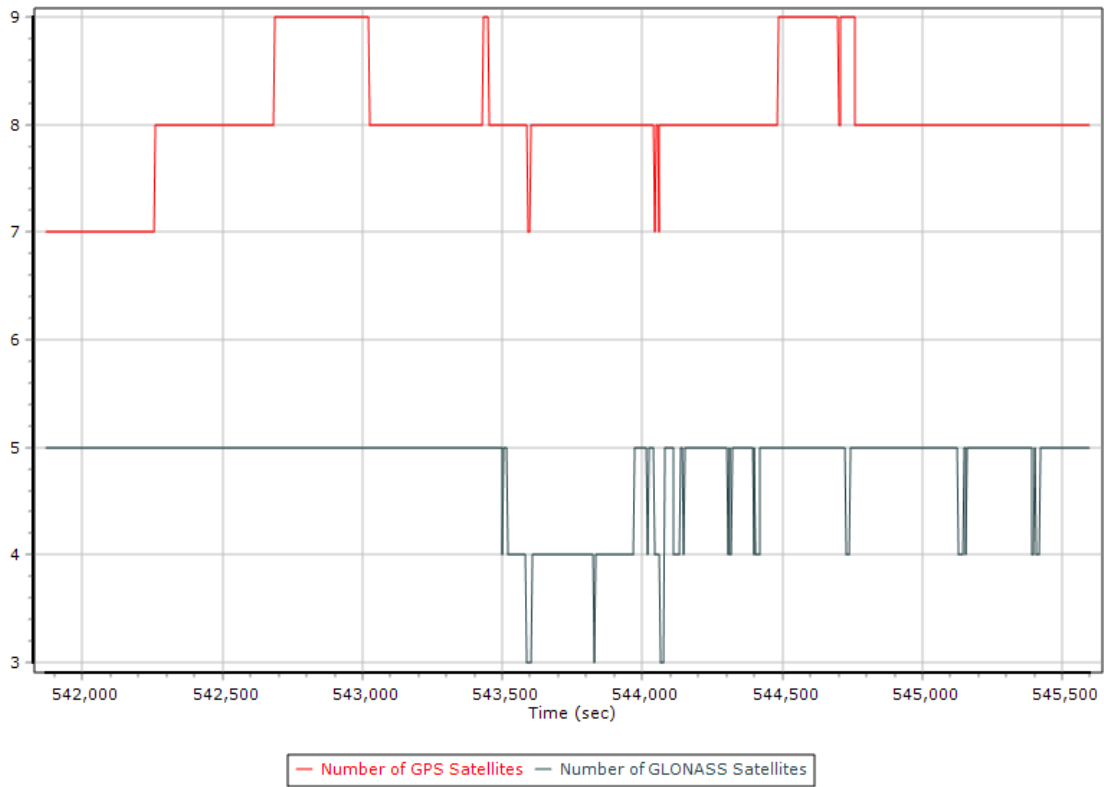
Seconds of start week

UTC Offset: 18.000

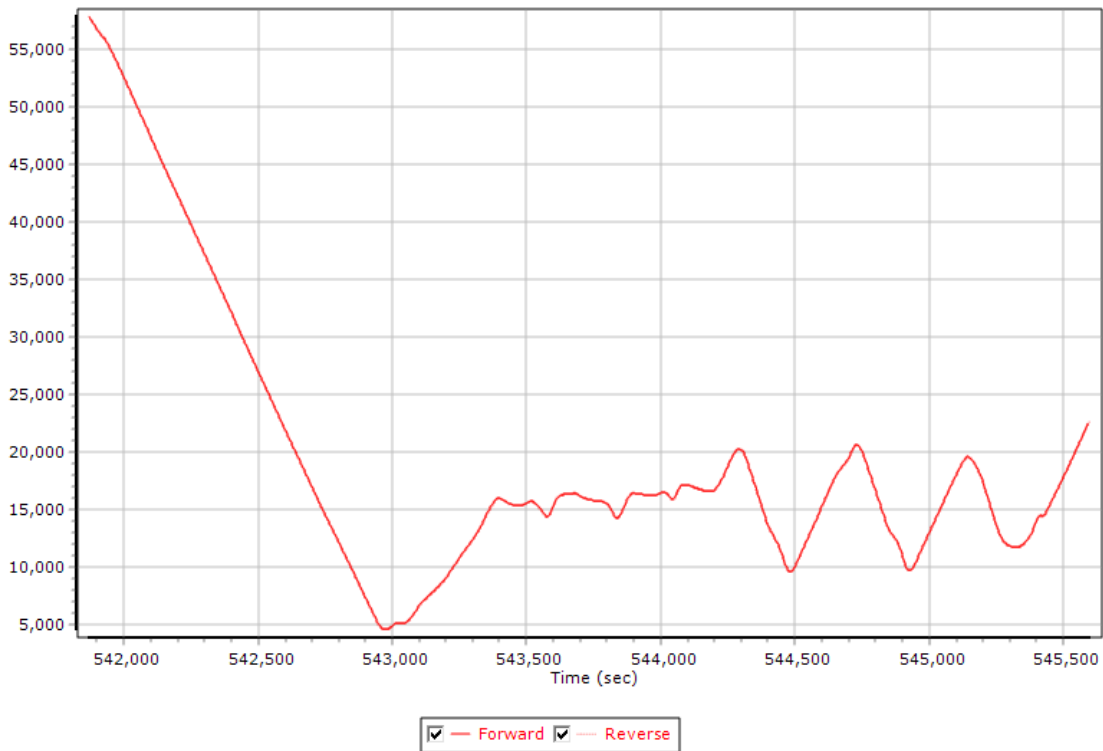
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

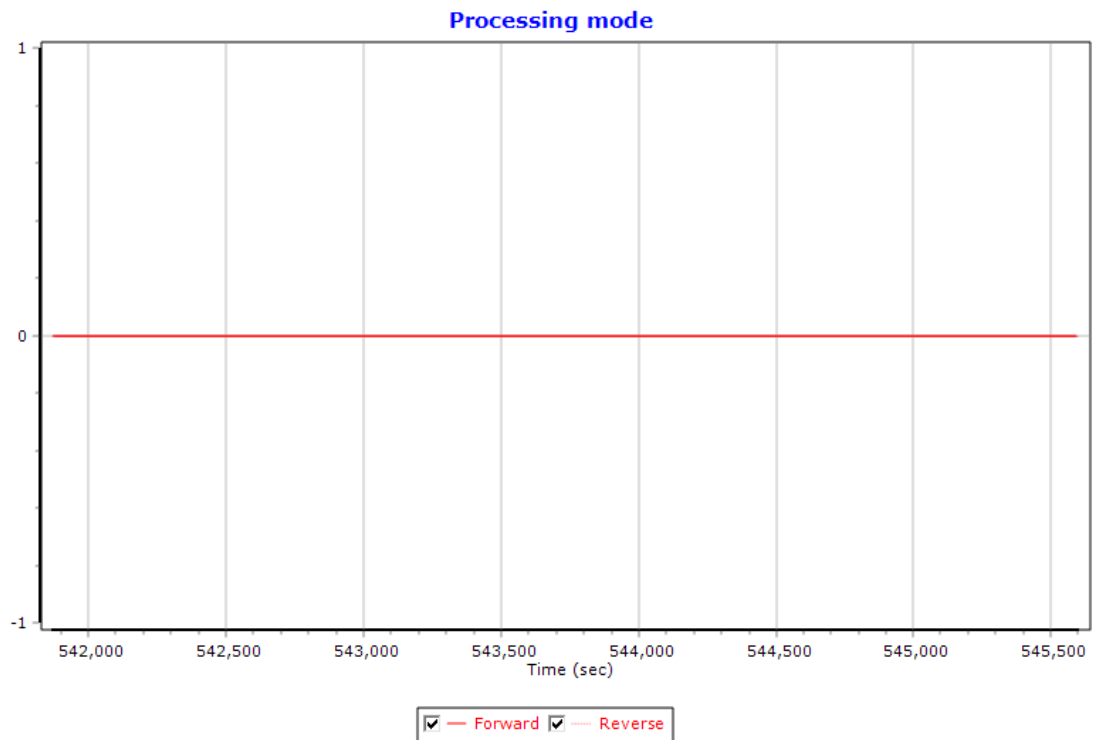
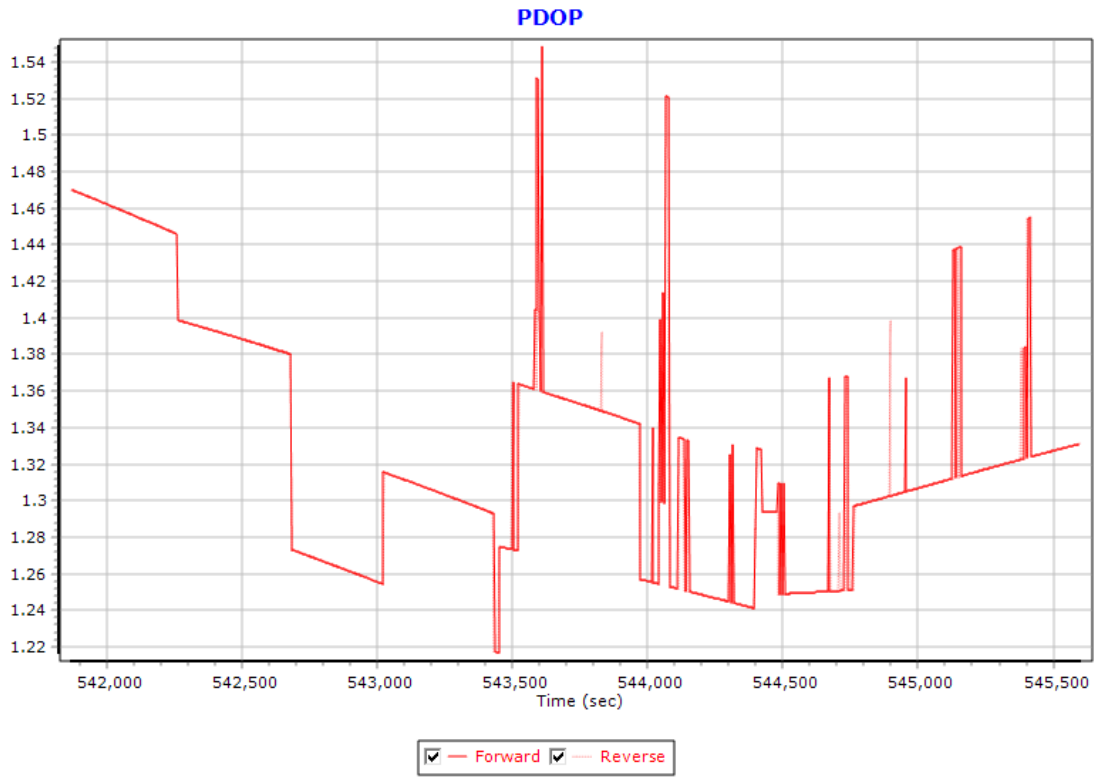






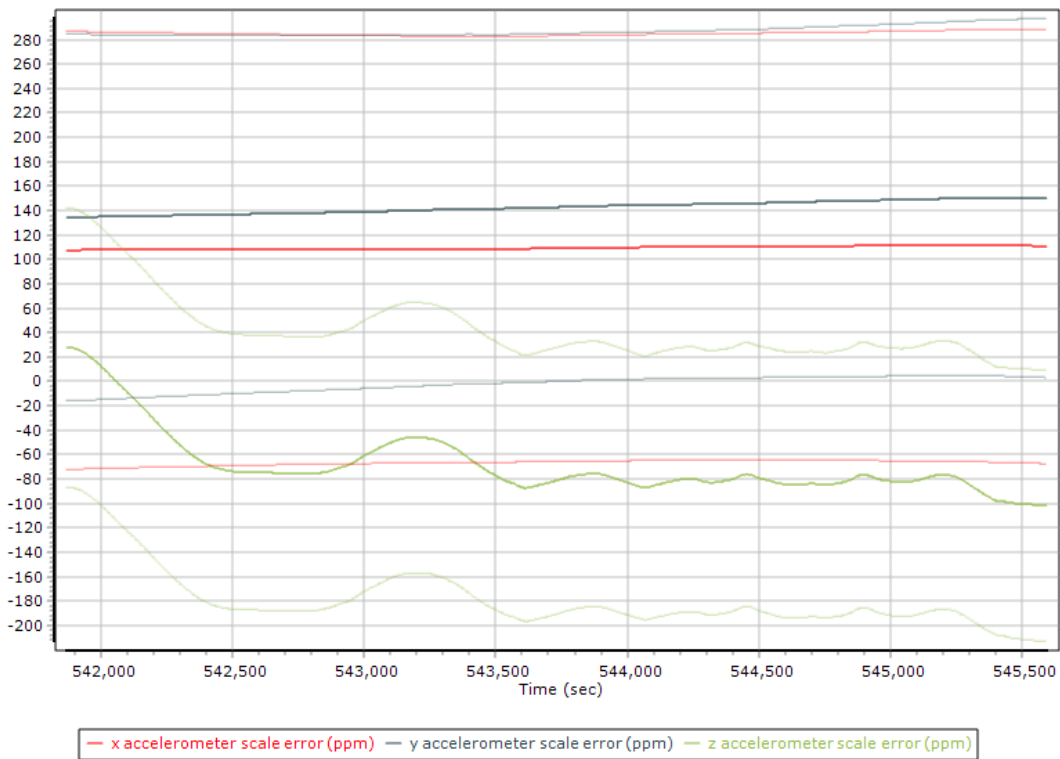
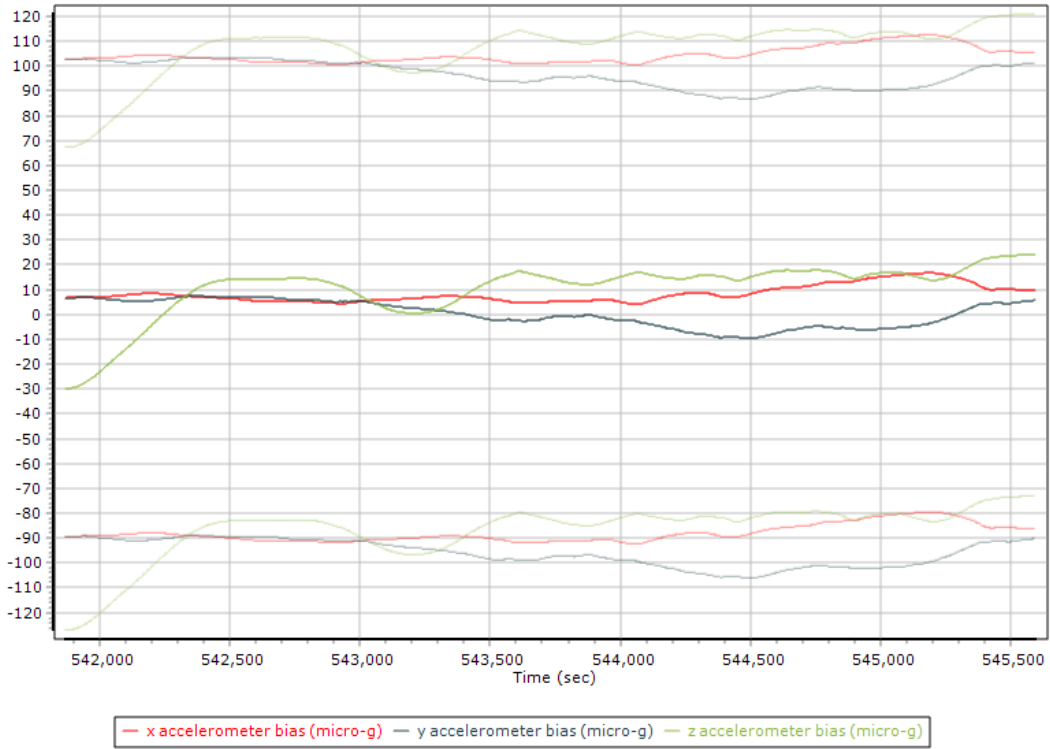
Baseline Length (m)

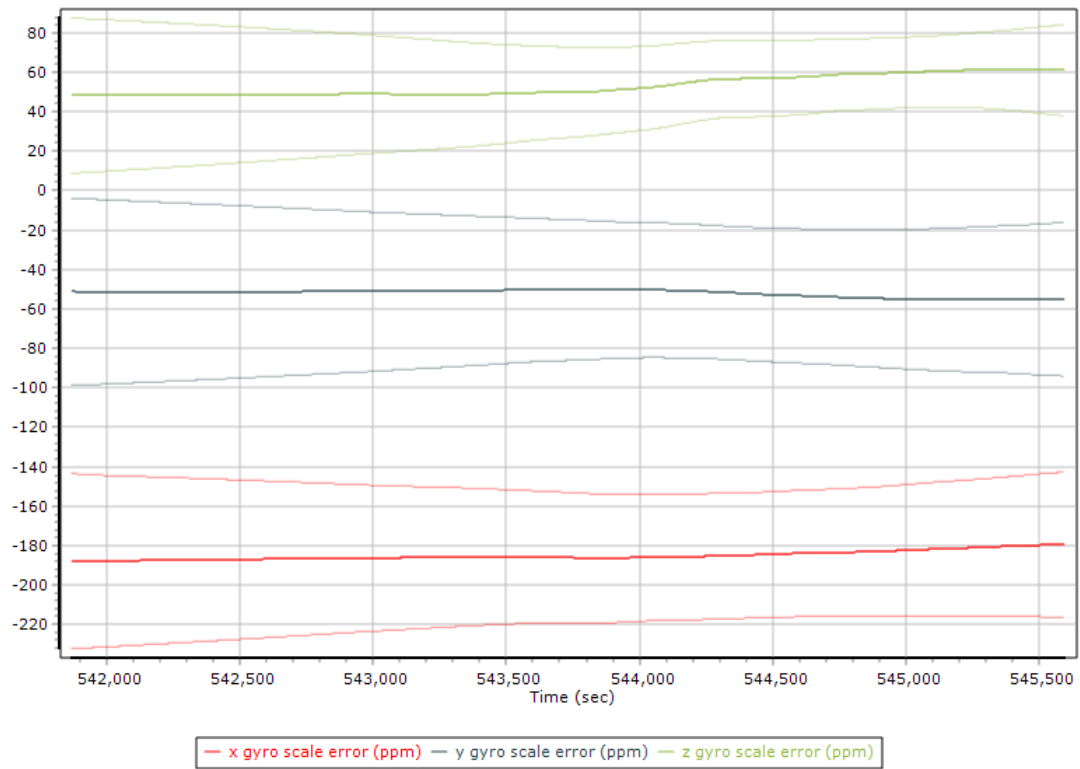
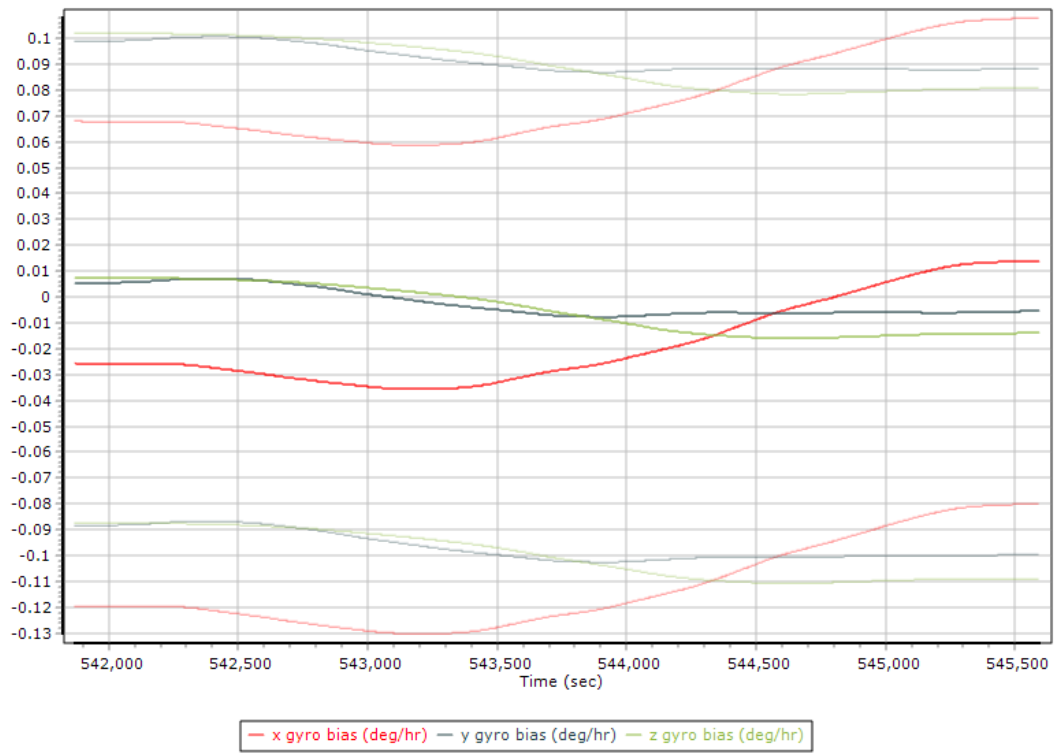




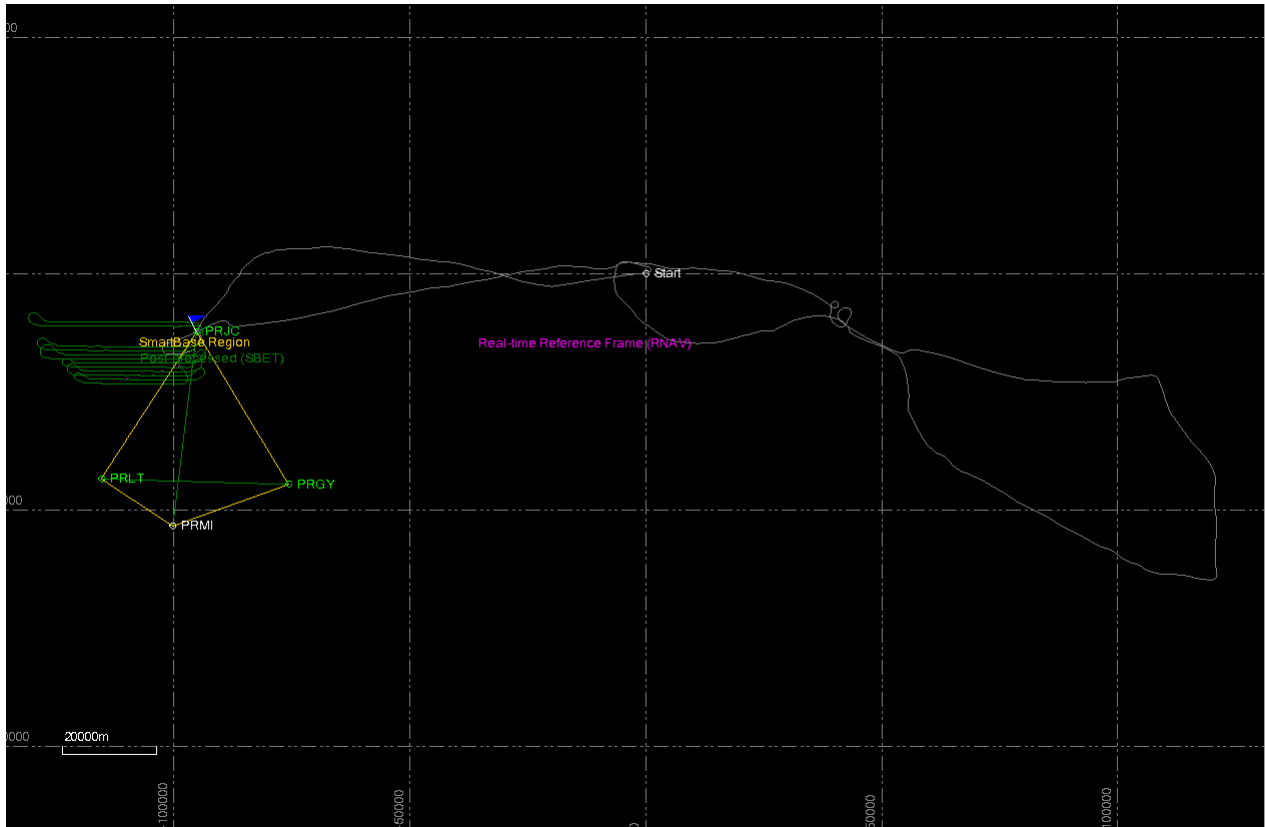
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





AZT18132B



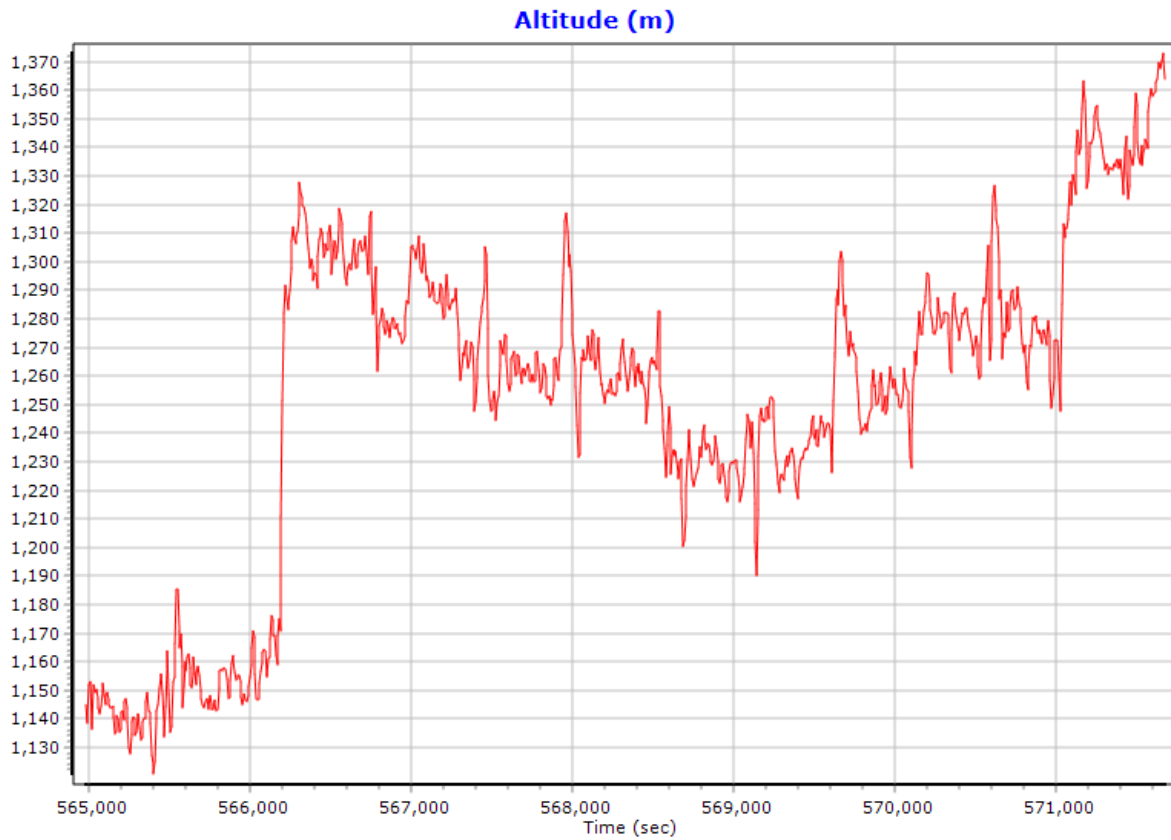
Stabilized Mount to IMU Lever Arm	Stabilized Mount to IMU Mounting Angles
X: -0.034 m	X: 0.000 deg
Y: -0.010 m	Y: 0.000 deg
Z: -0.352 m	Z: 0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	Aircraft to Stabilized Mount Mounting Angles
X: -0.049 m	X: 0.000 deg
Y: 0.003 m	Y: 0.000 deg
Z: -0.738 m	Z: 0.000 deg
Standard Deviation: <3cm 10cm 50cm 1m 10m	

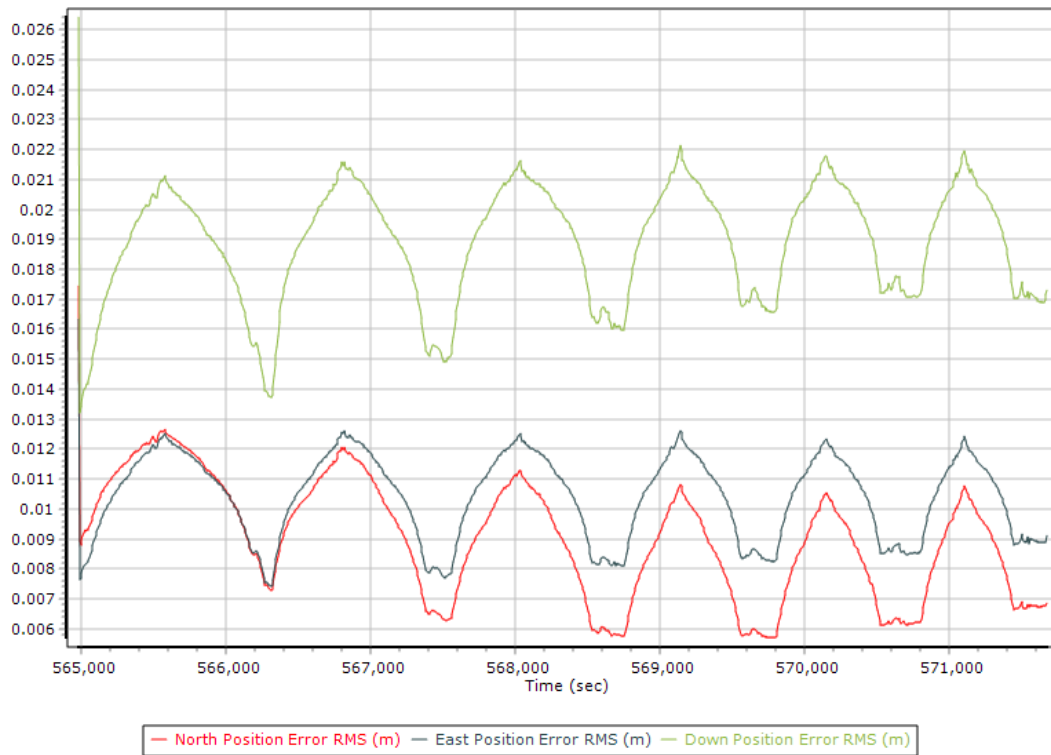
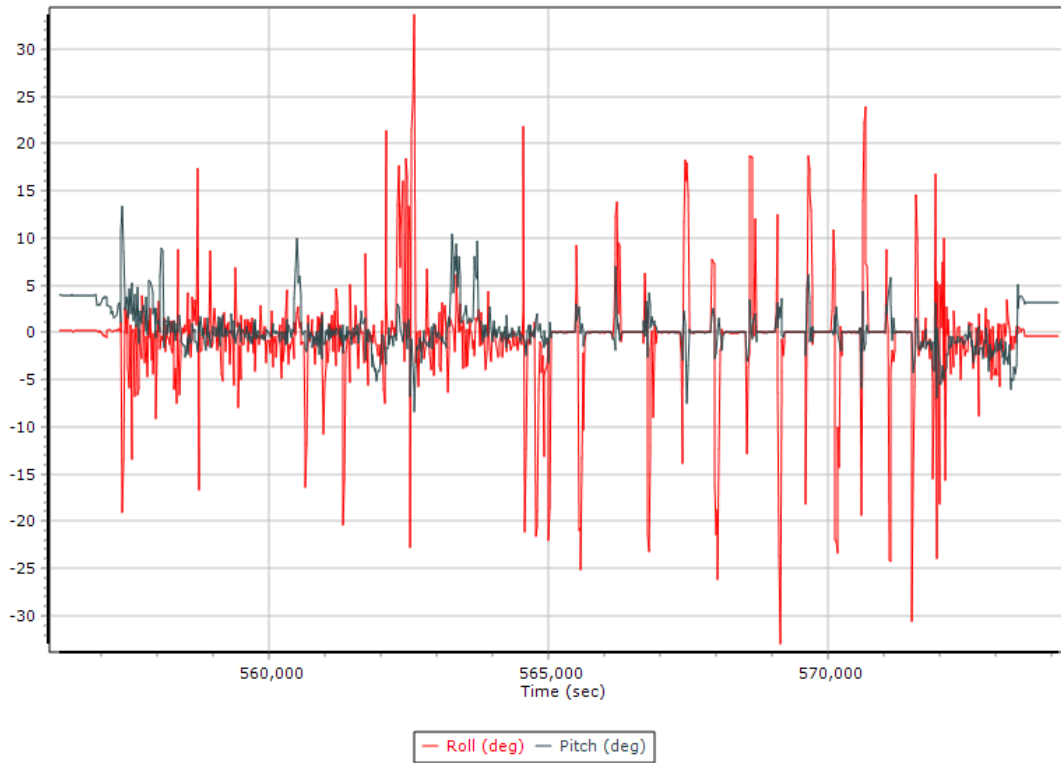
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

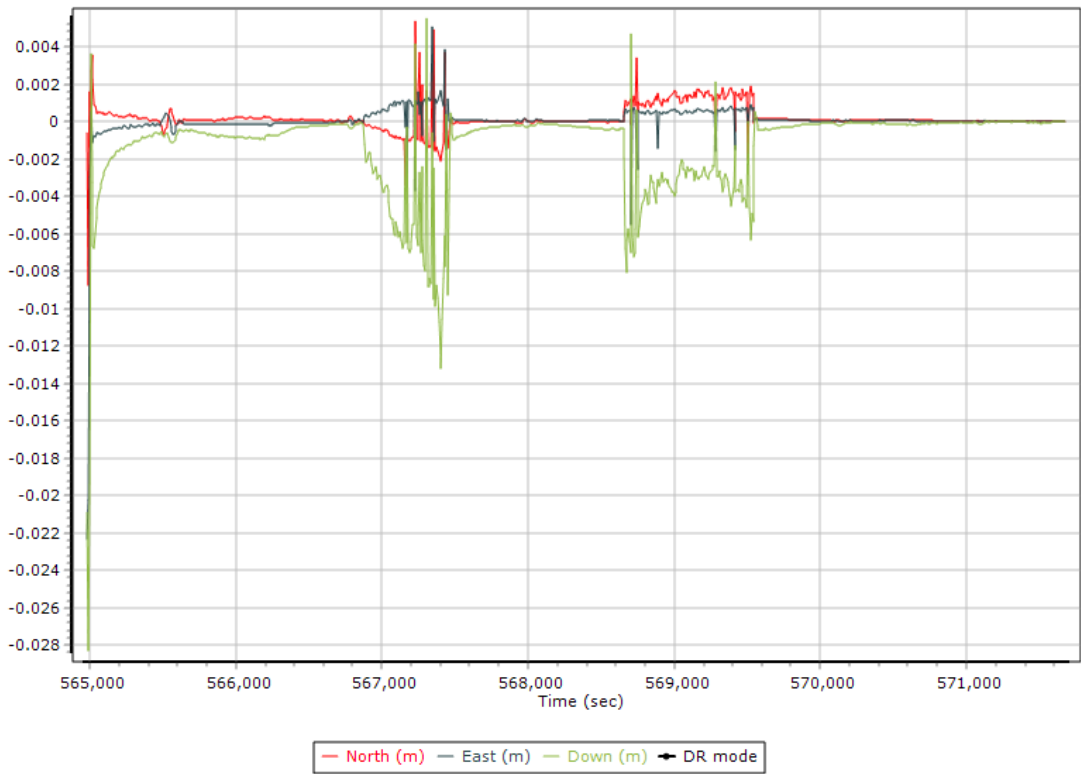
Timing

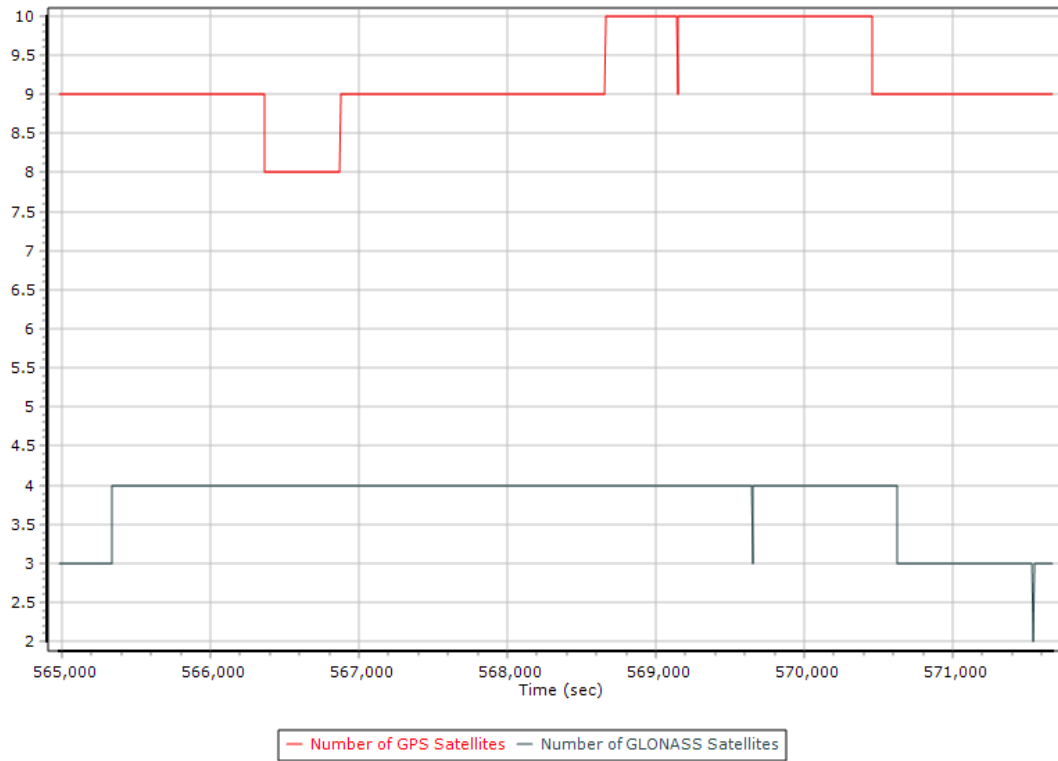
Start	564978.560	Data	Incr. (sec)
End	571685.449	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset 18.000

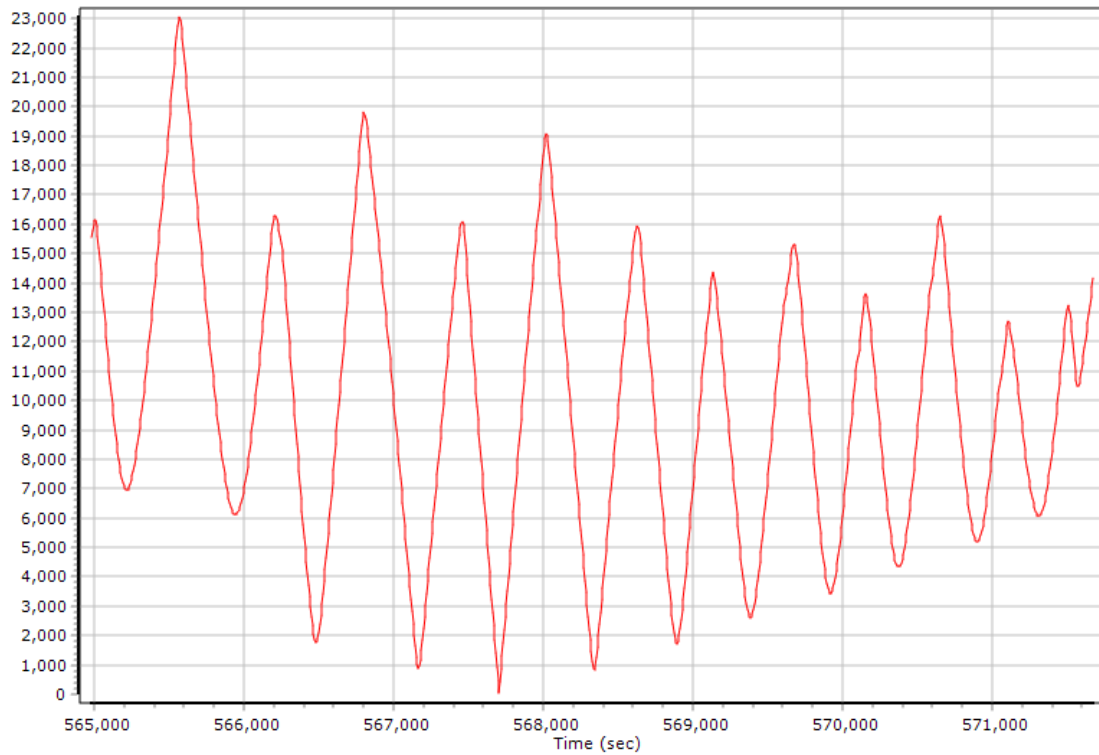


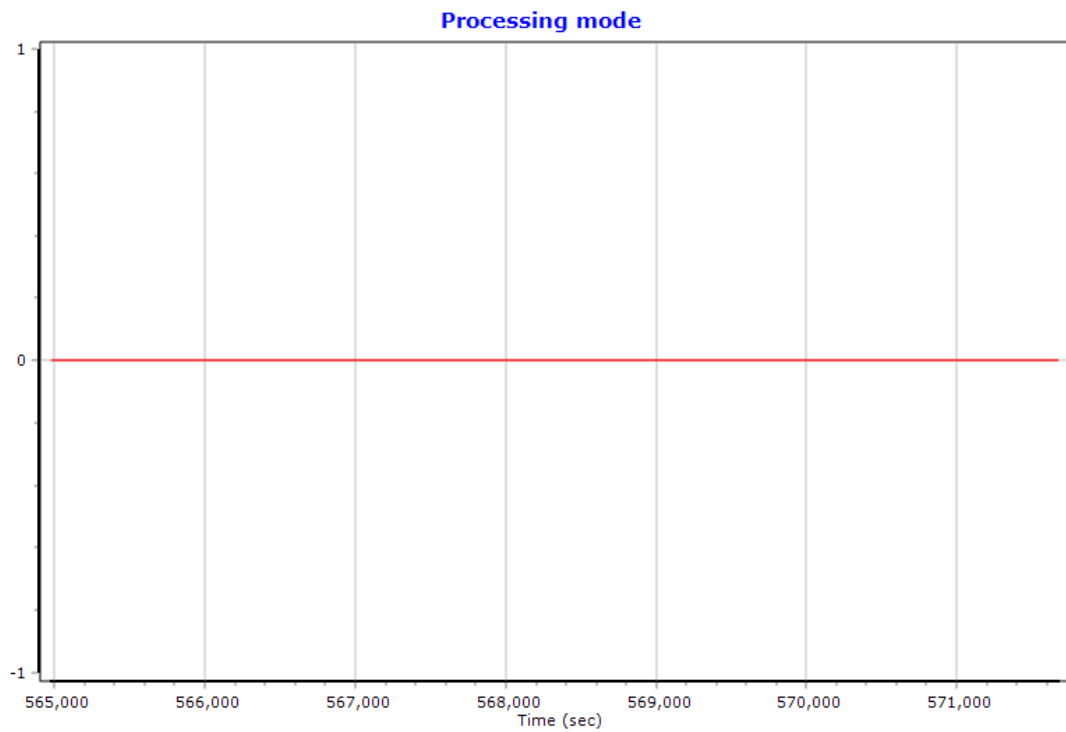
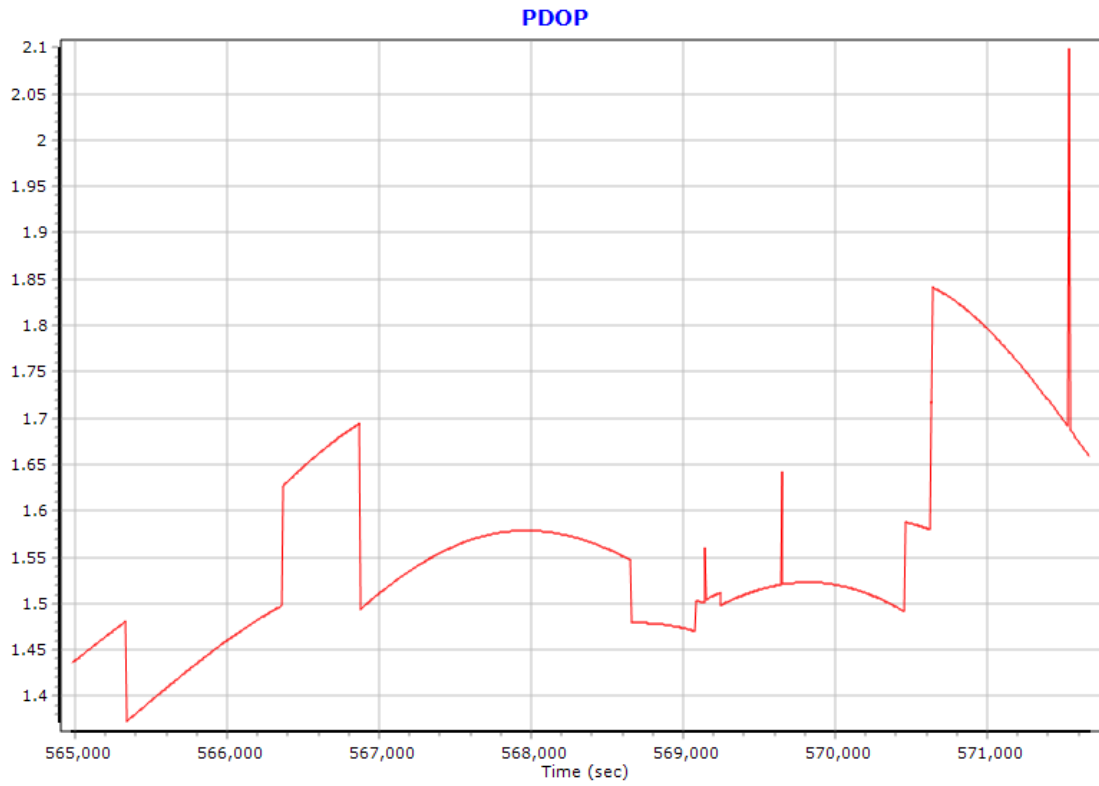






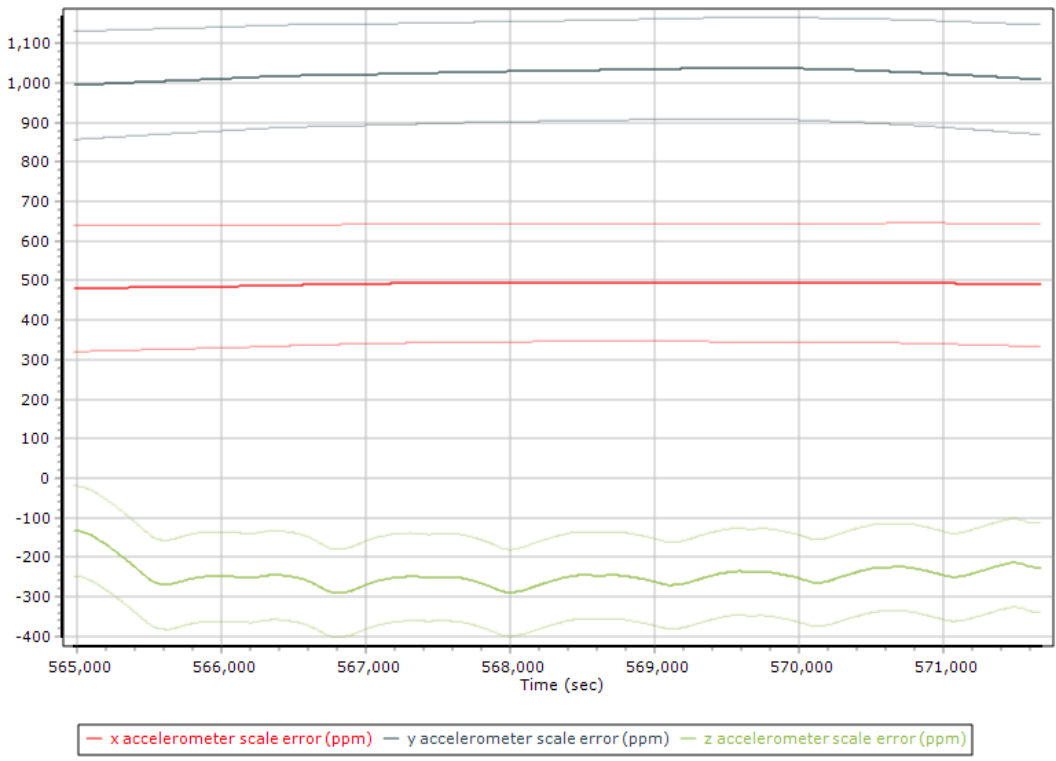
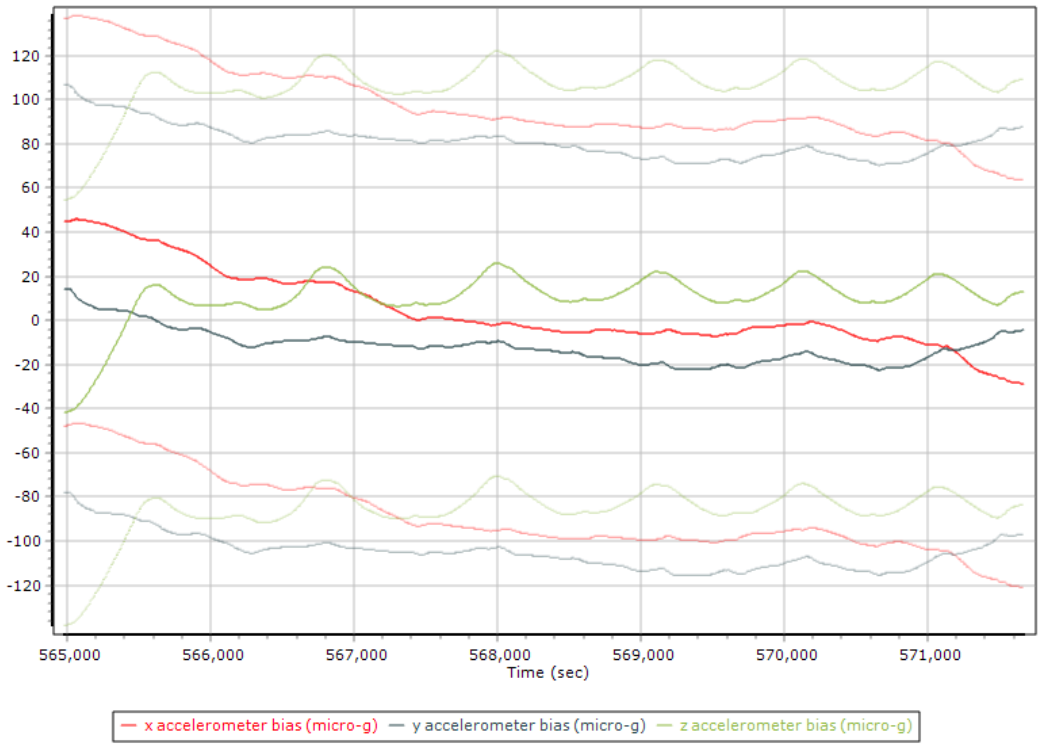
Baseline Length (m)

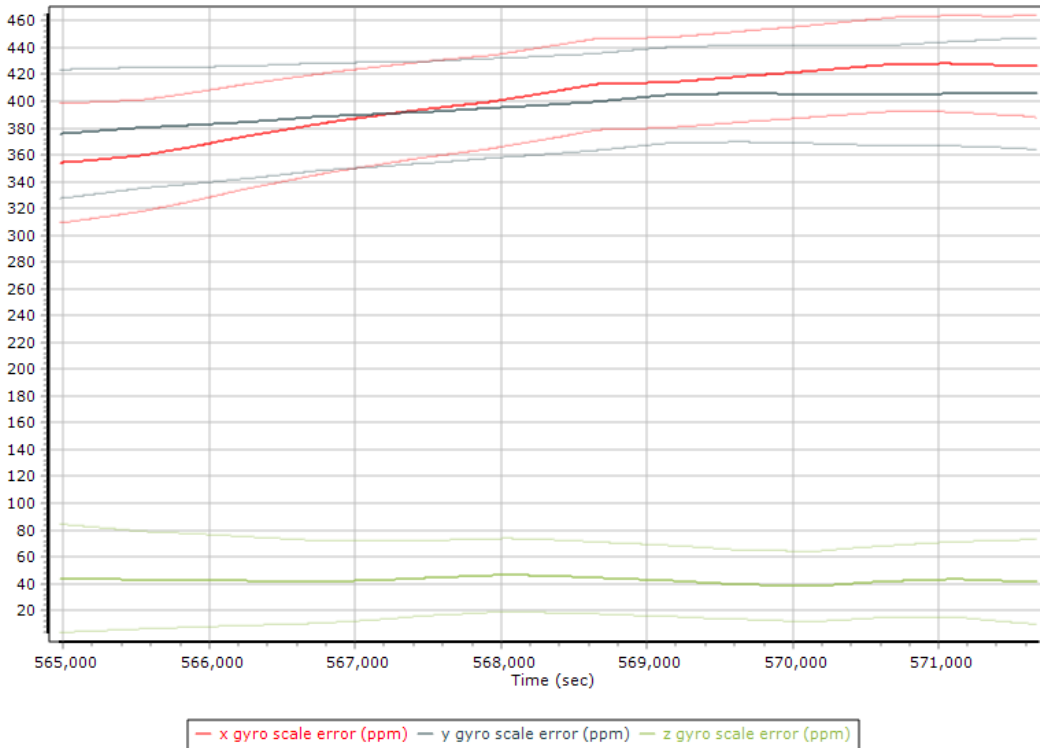
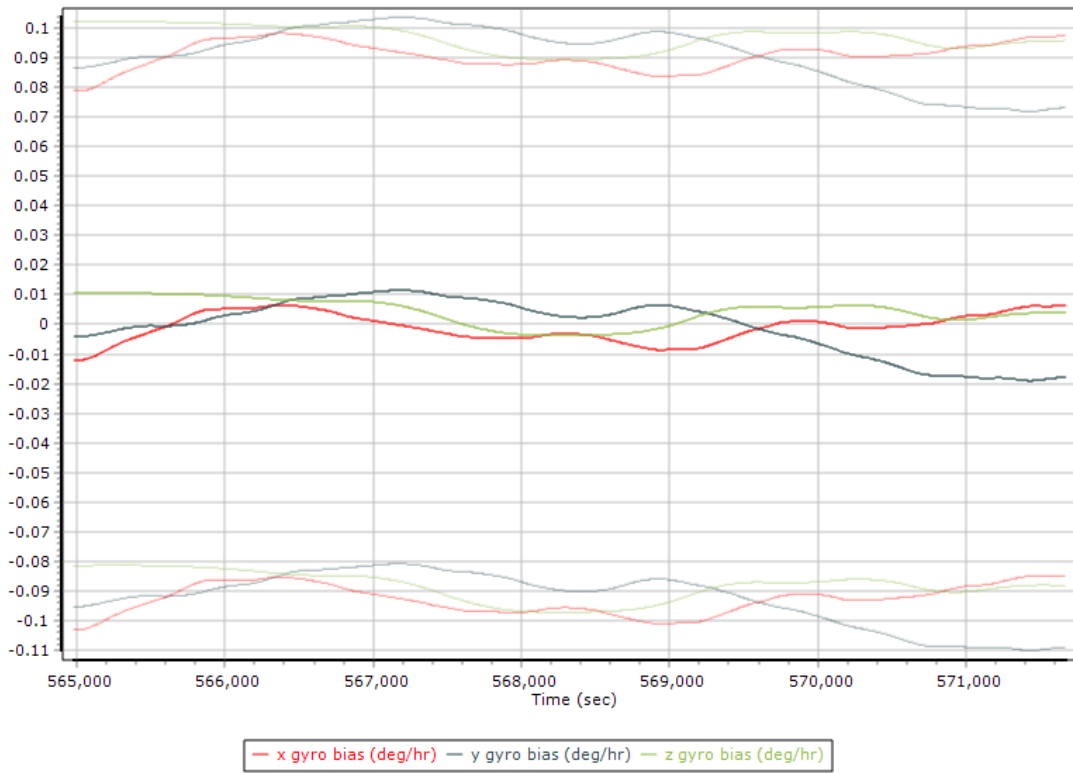




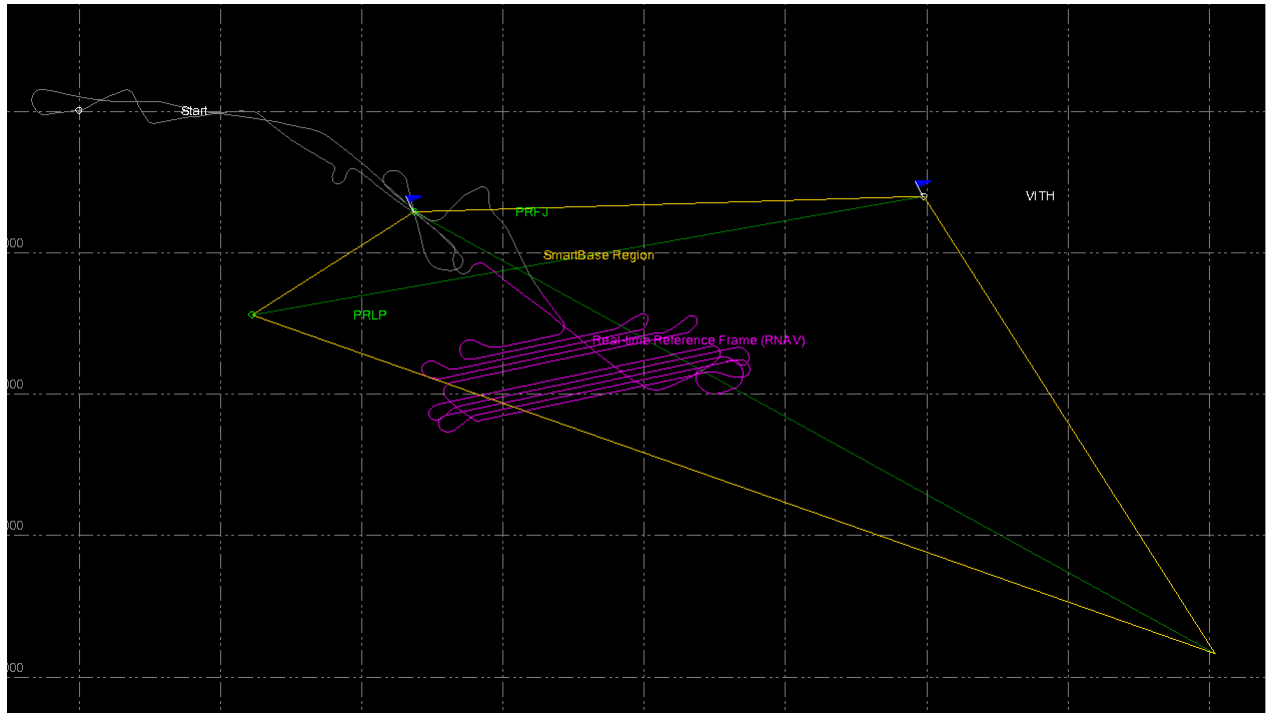
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





AZT18132C



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

Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.049 m	0.003 m	-1.230 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

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

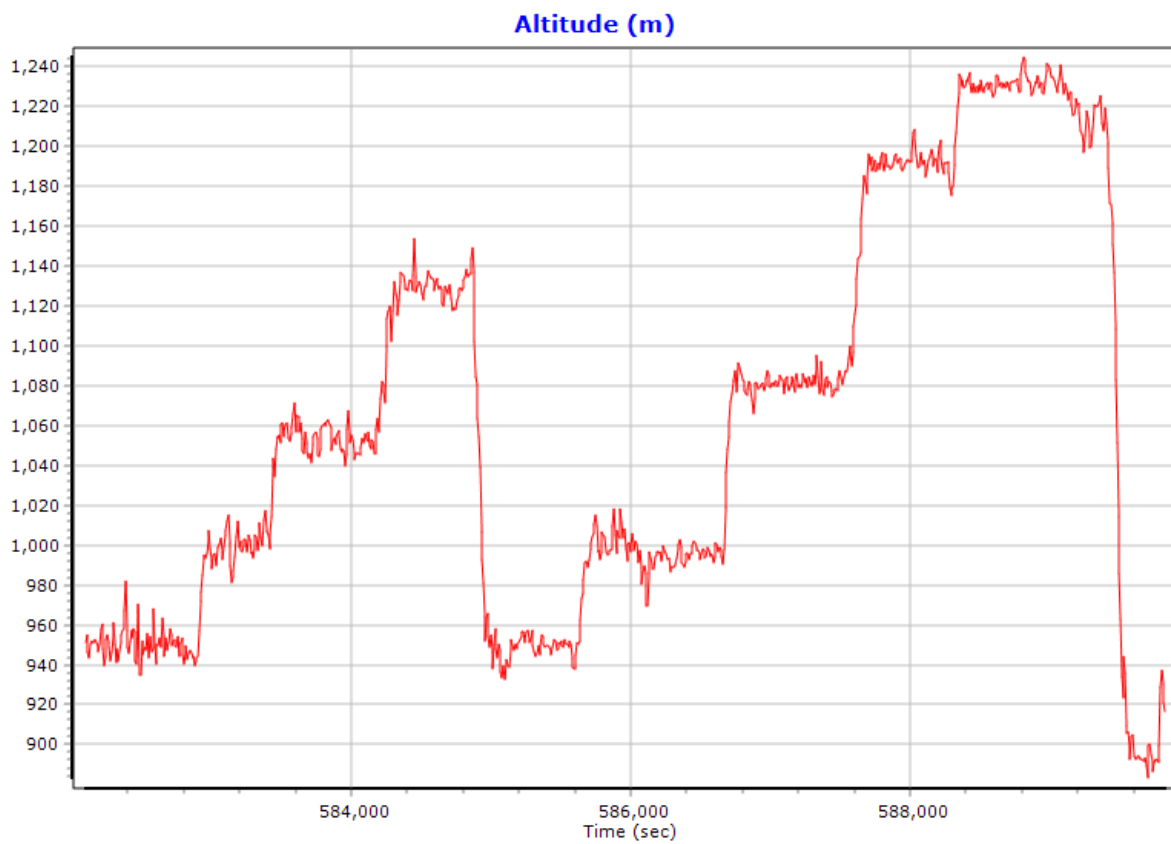
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

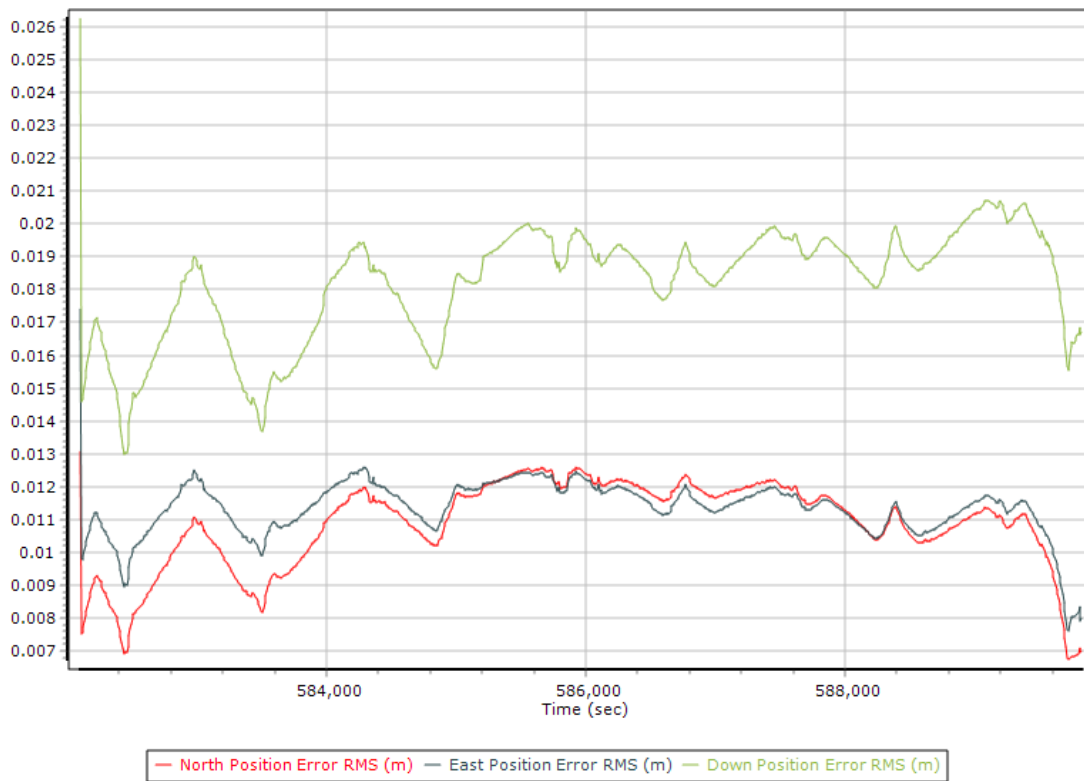
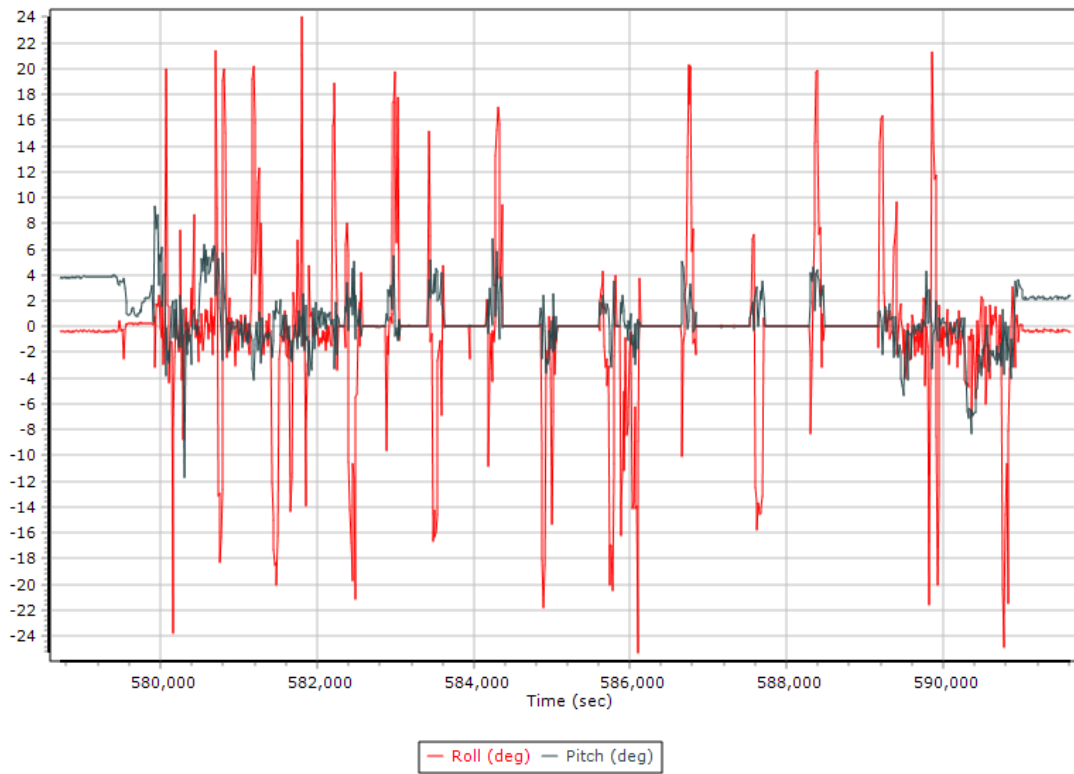
OK Cancel

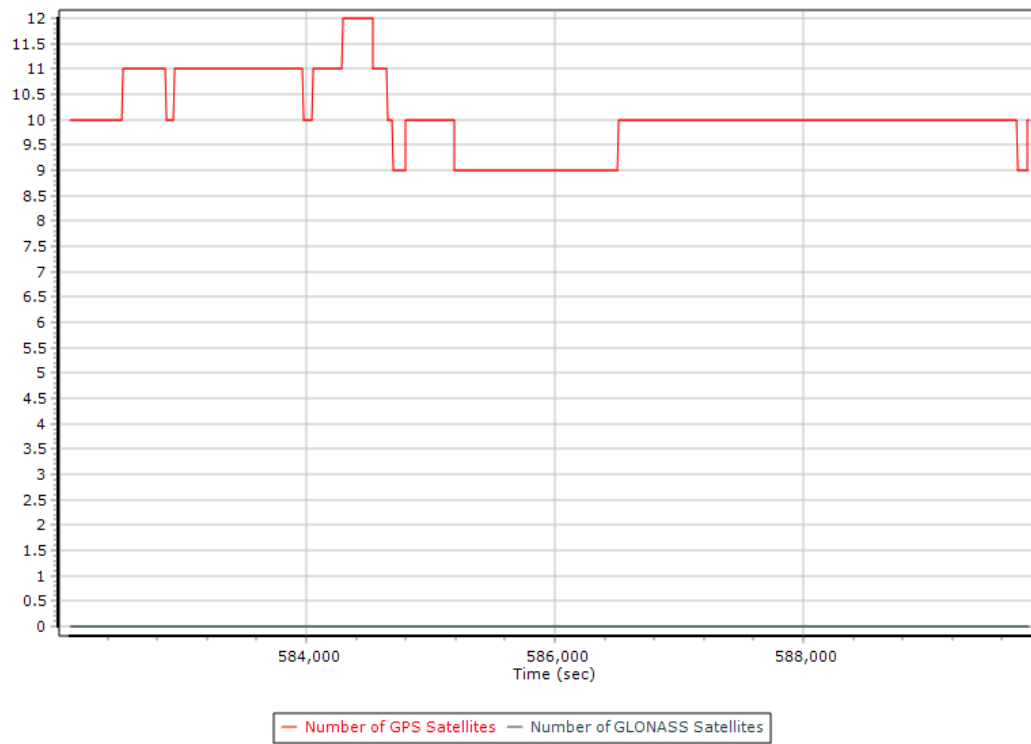
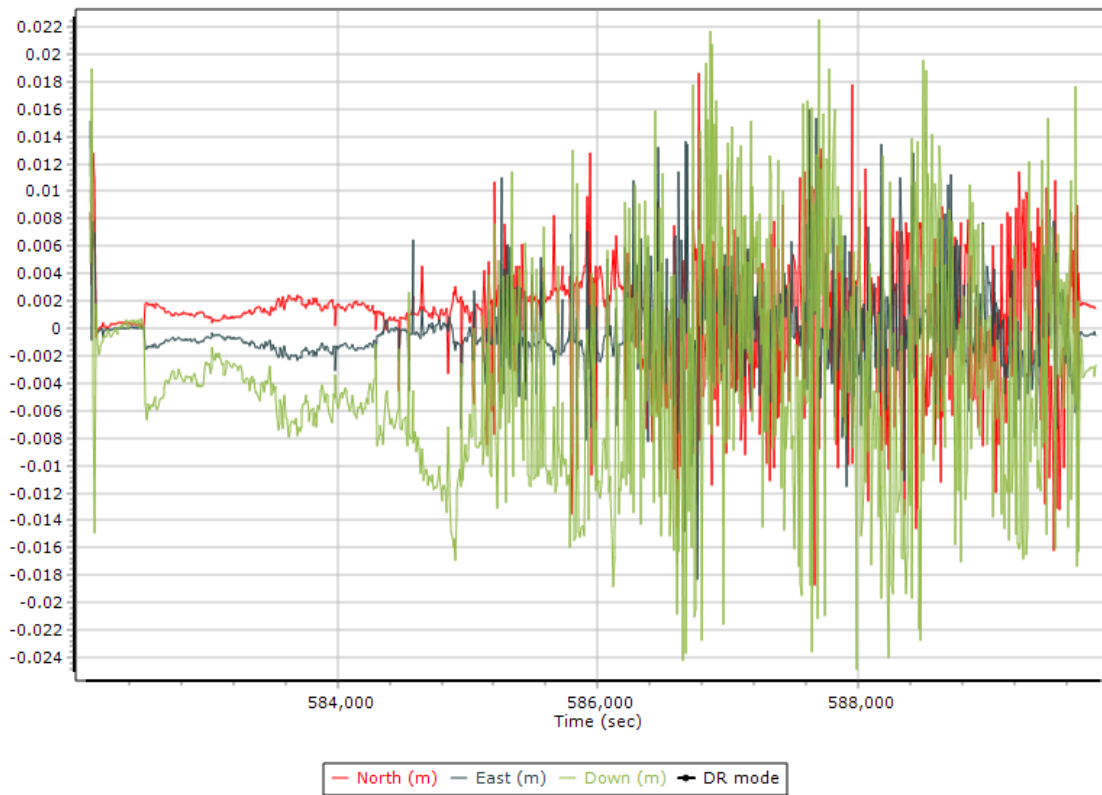
Timing

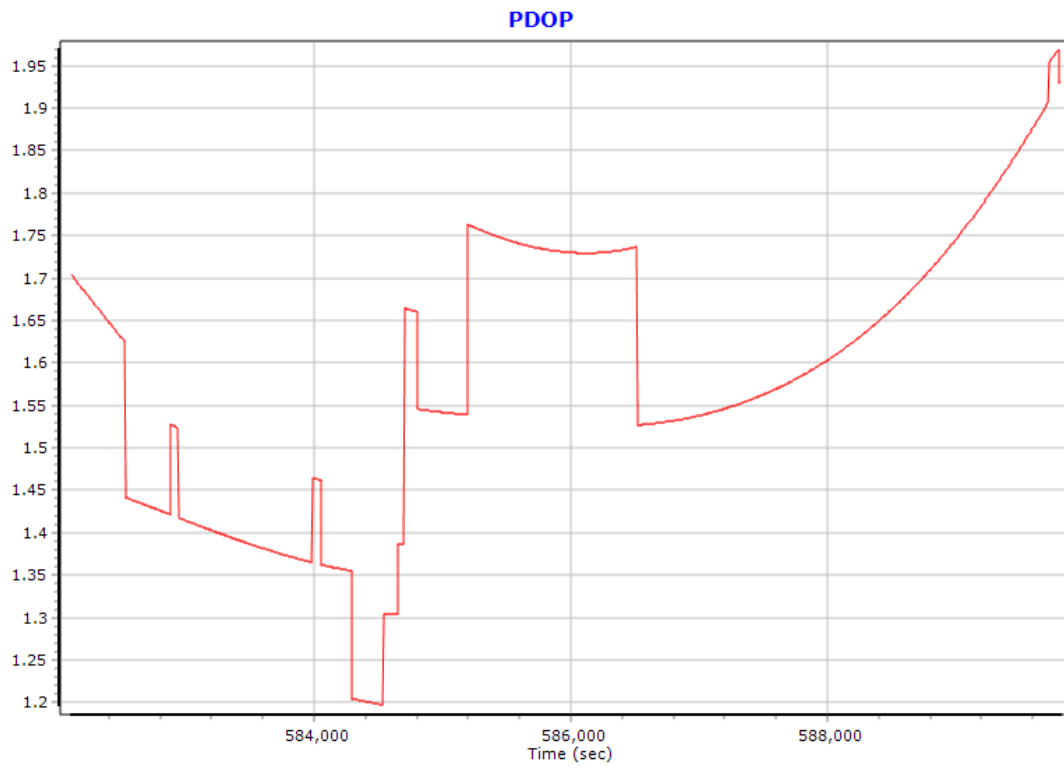
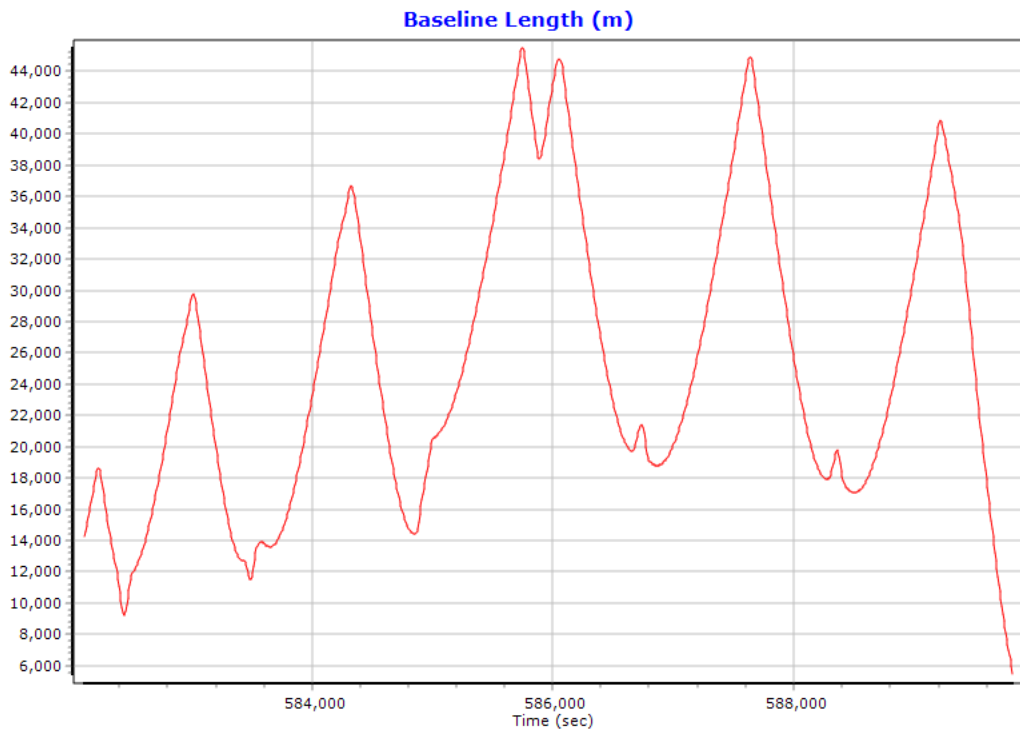
Start	582098.166	Data	Incr. (sec)
End	589833.972	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

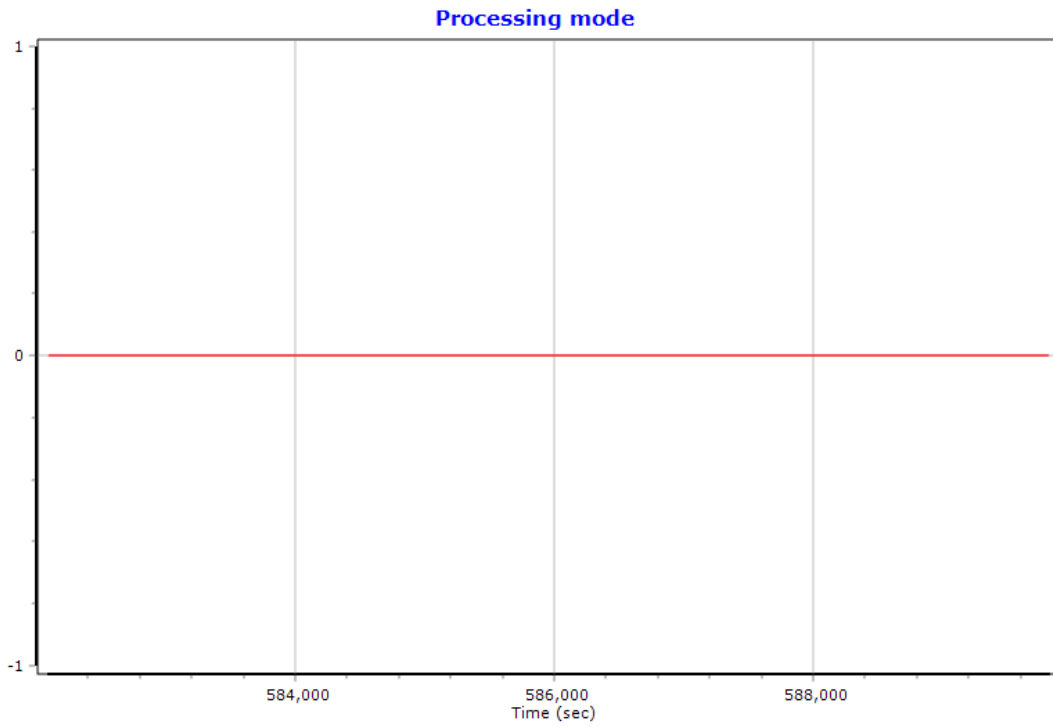
UTC Offset 18.000





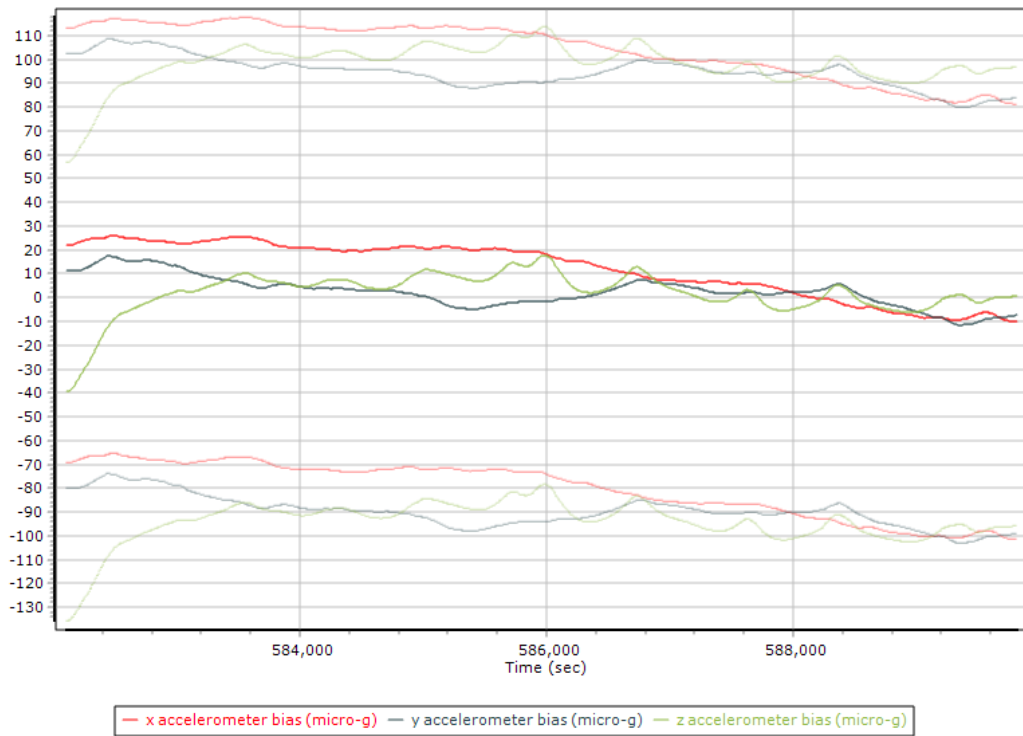
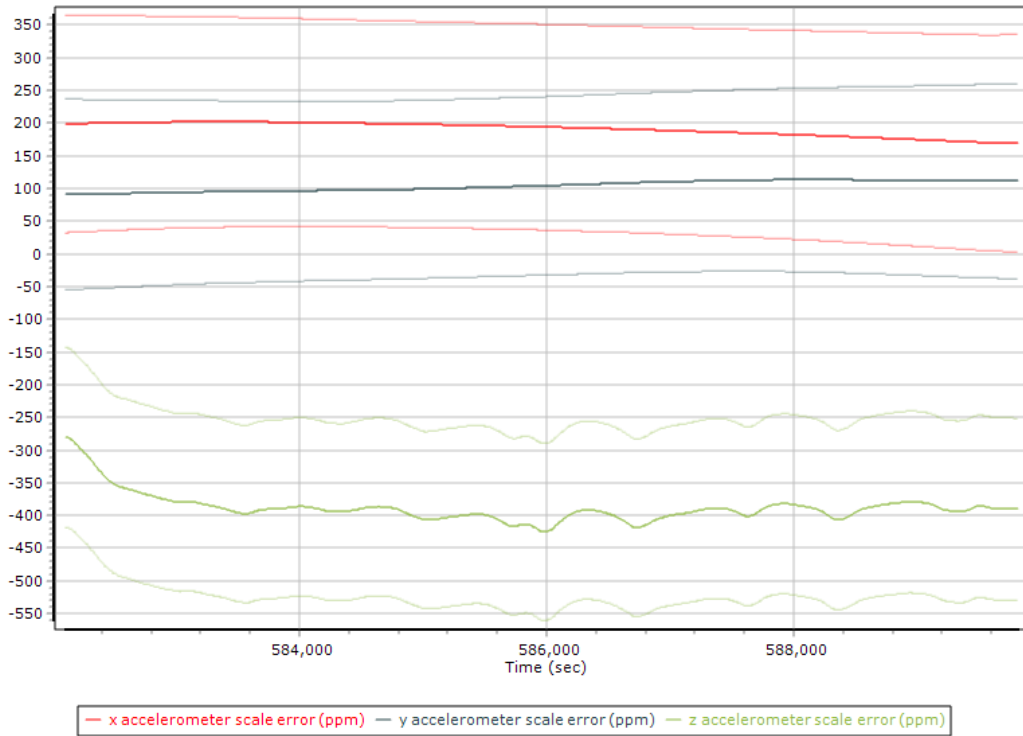


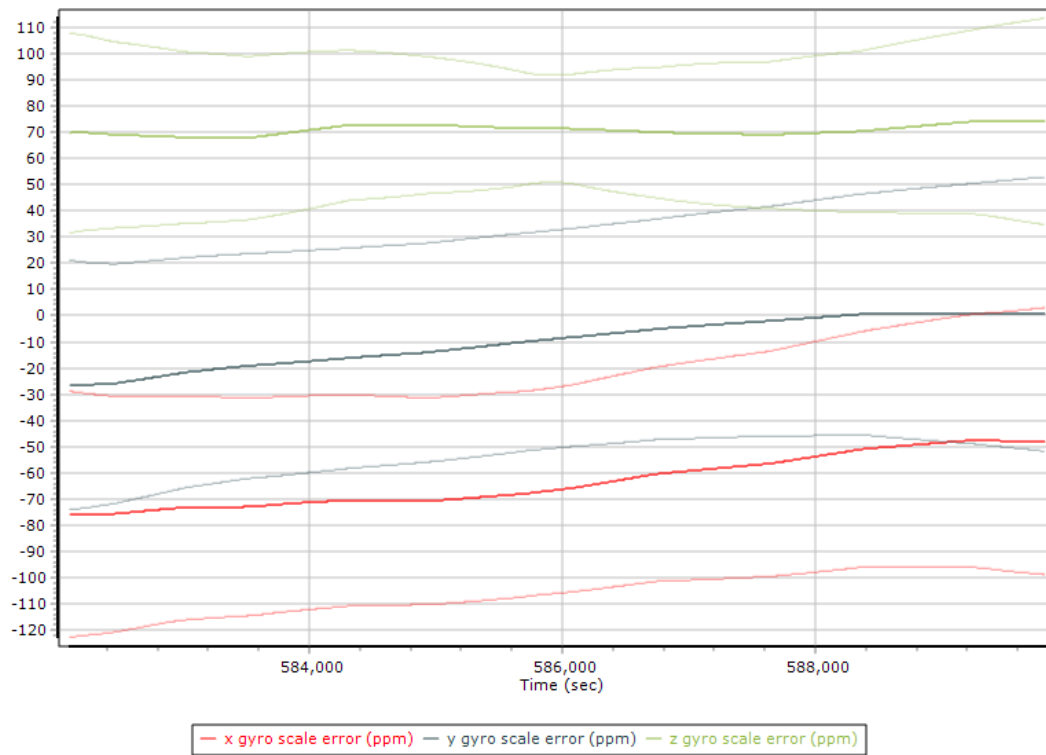
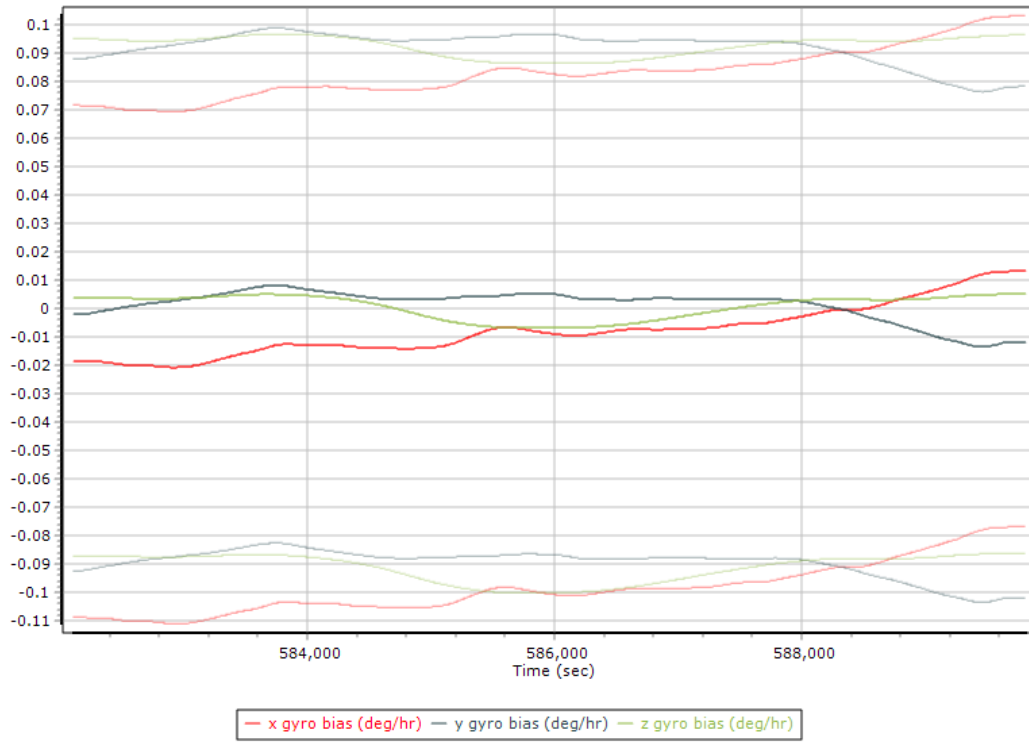




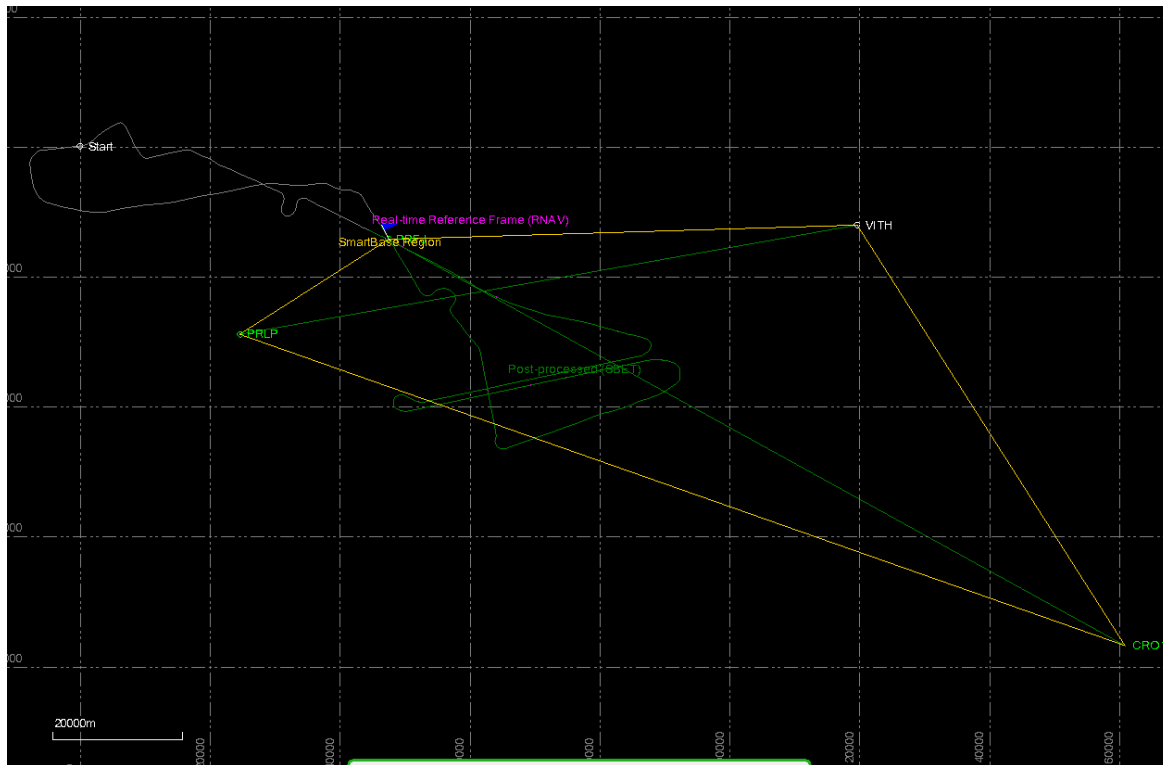
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





AZT18132D



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

Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.049 m	0.003 m	-1.230 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	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

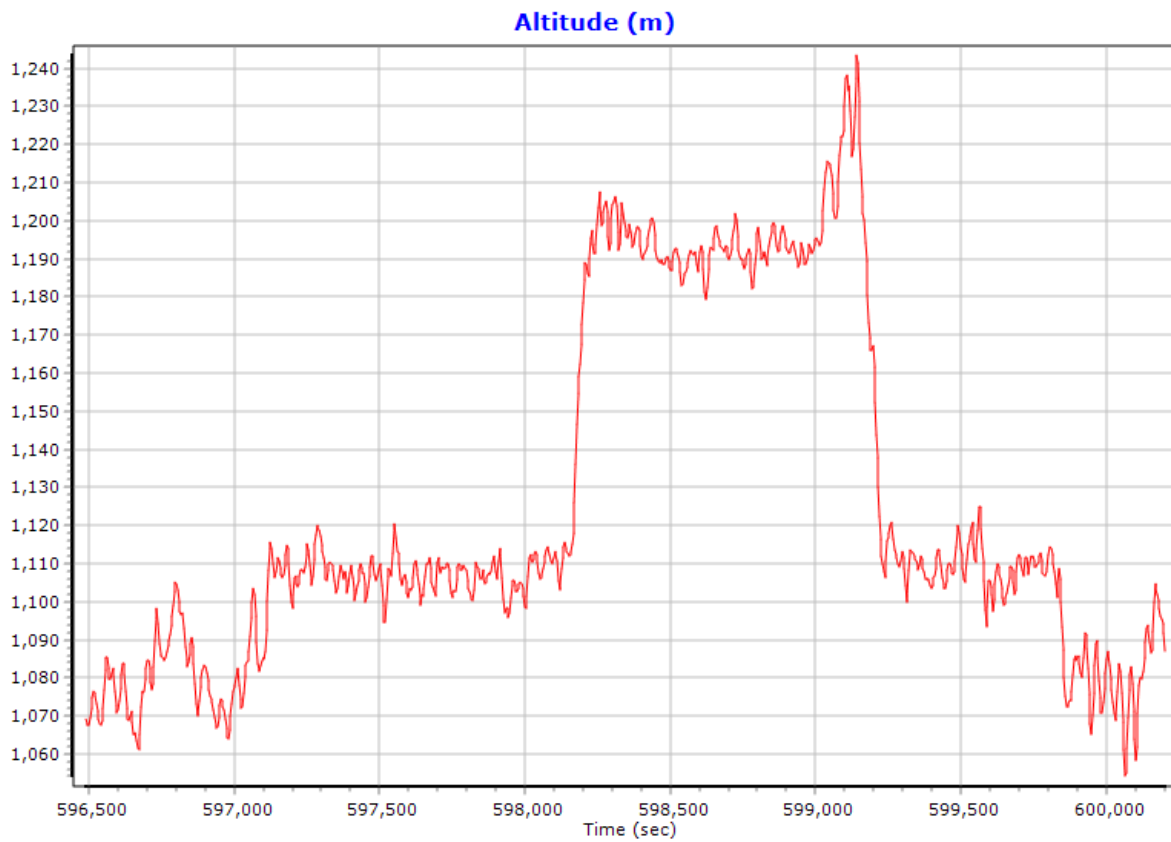
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
Timing
Algorithms
Initialization
Lever Arms and Mounting Angles
Export
Camera
LiDAR
SAR

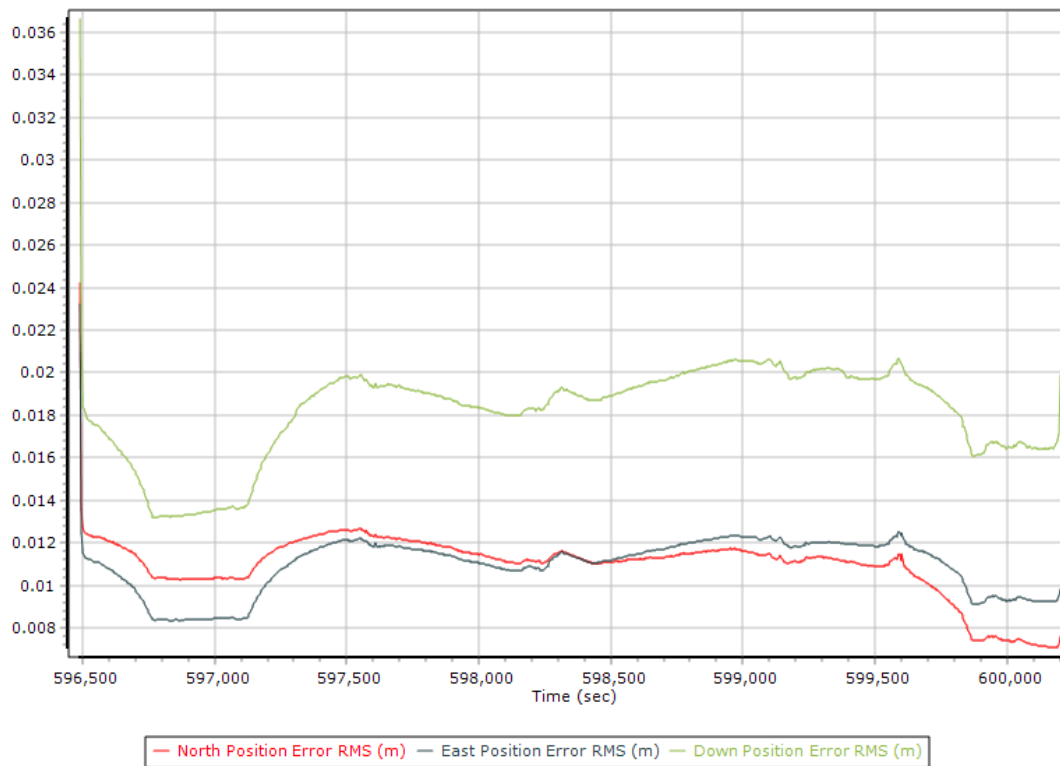
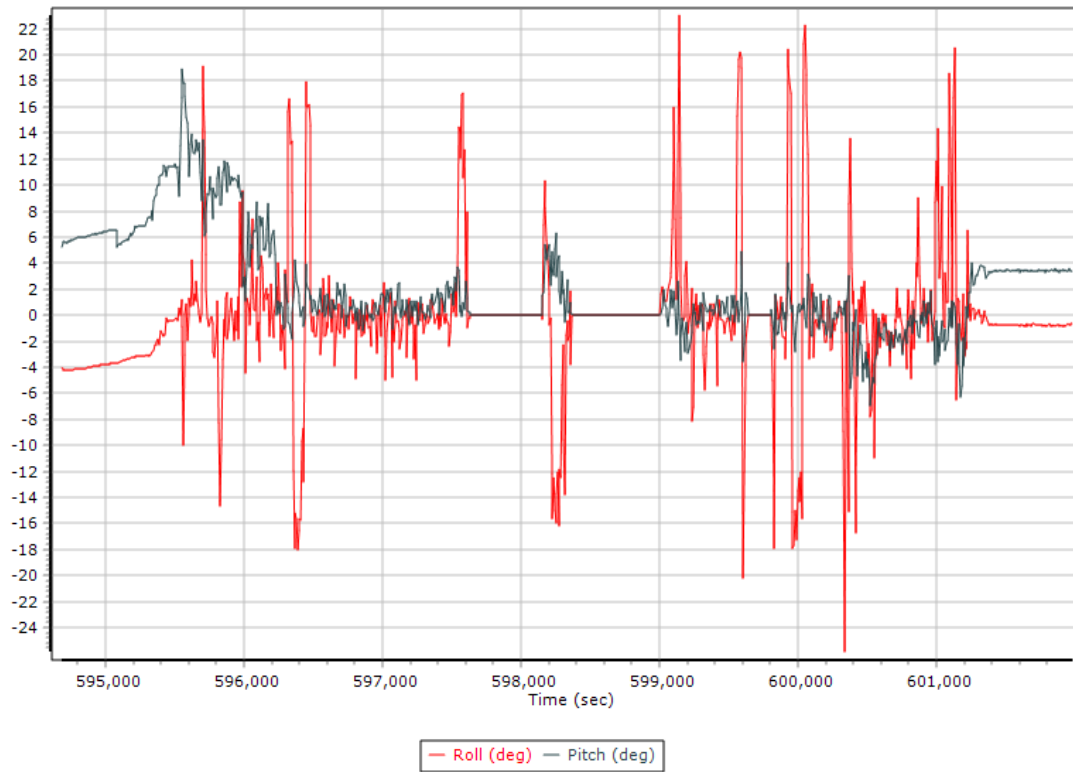
Timing

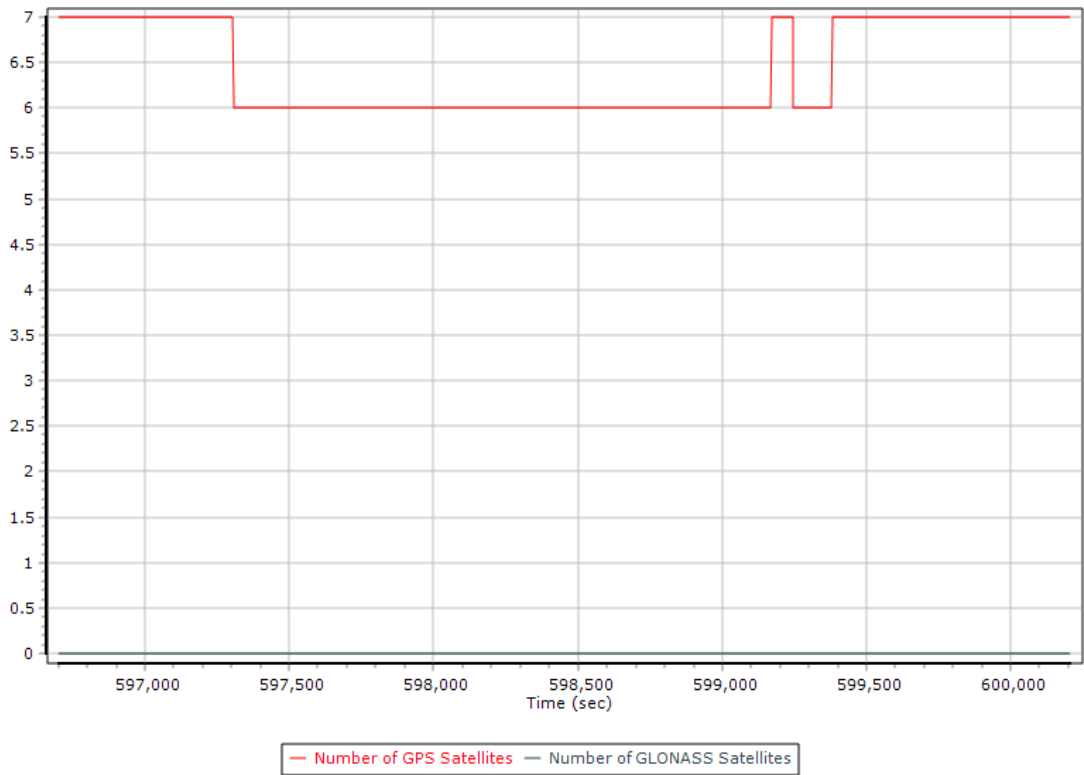
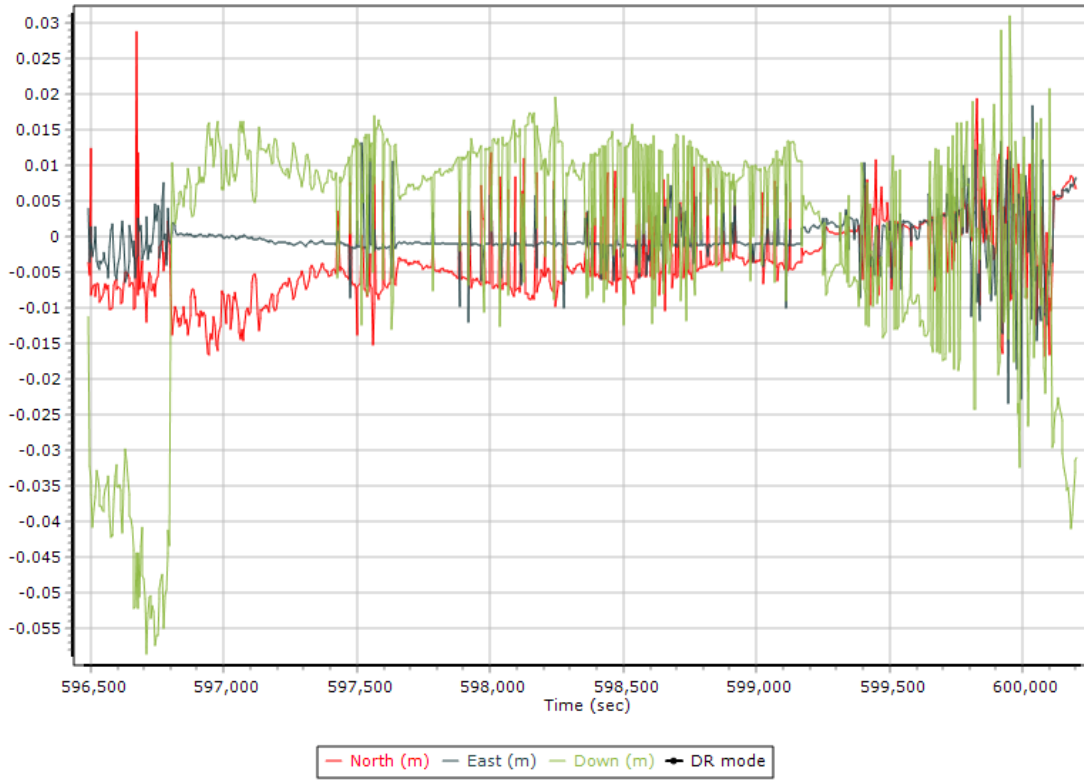
Start: 596487.041
End: 600207.908
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

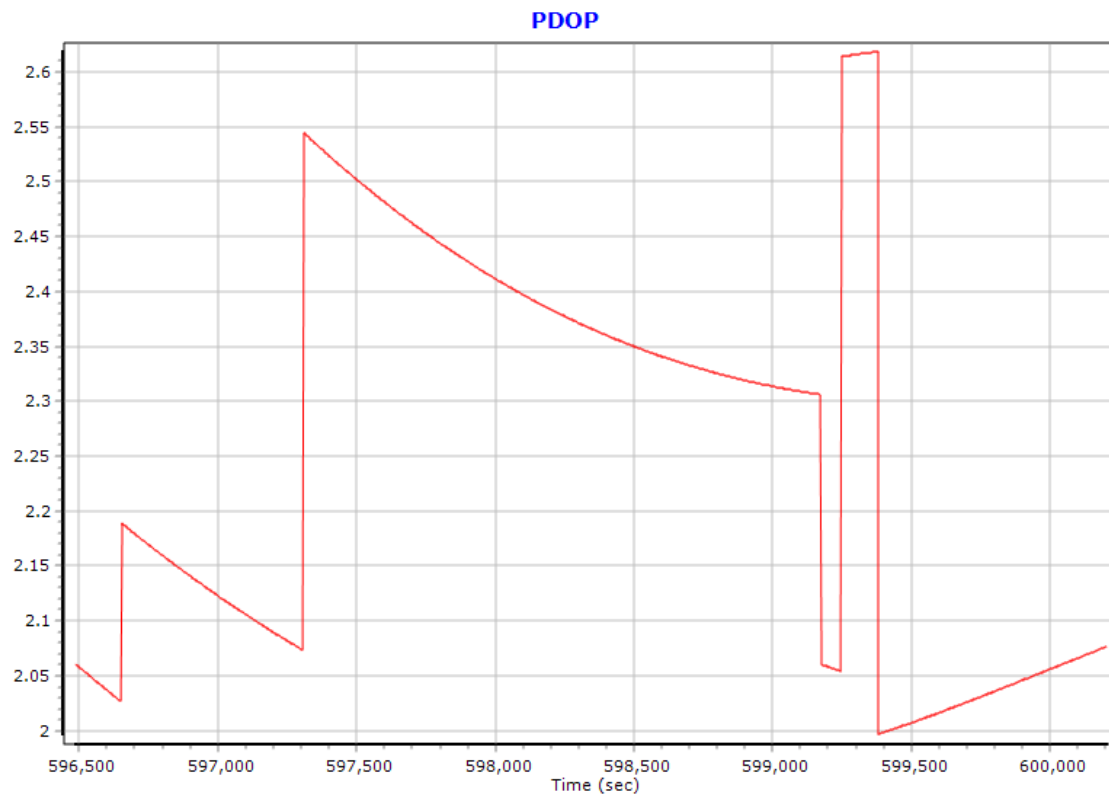
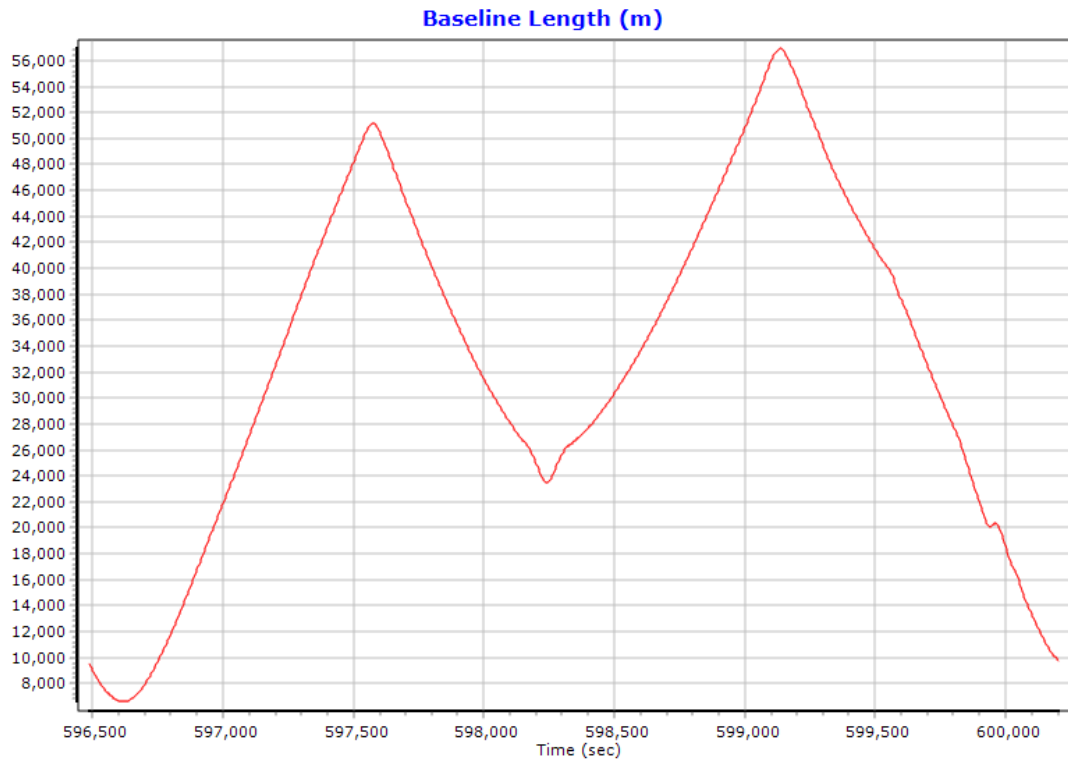
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

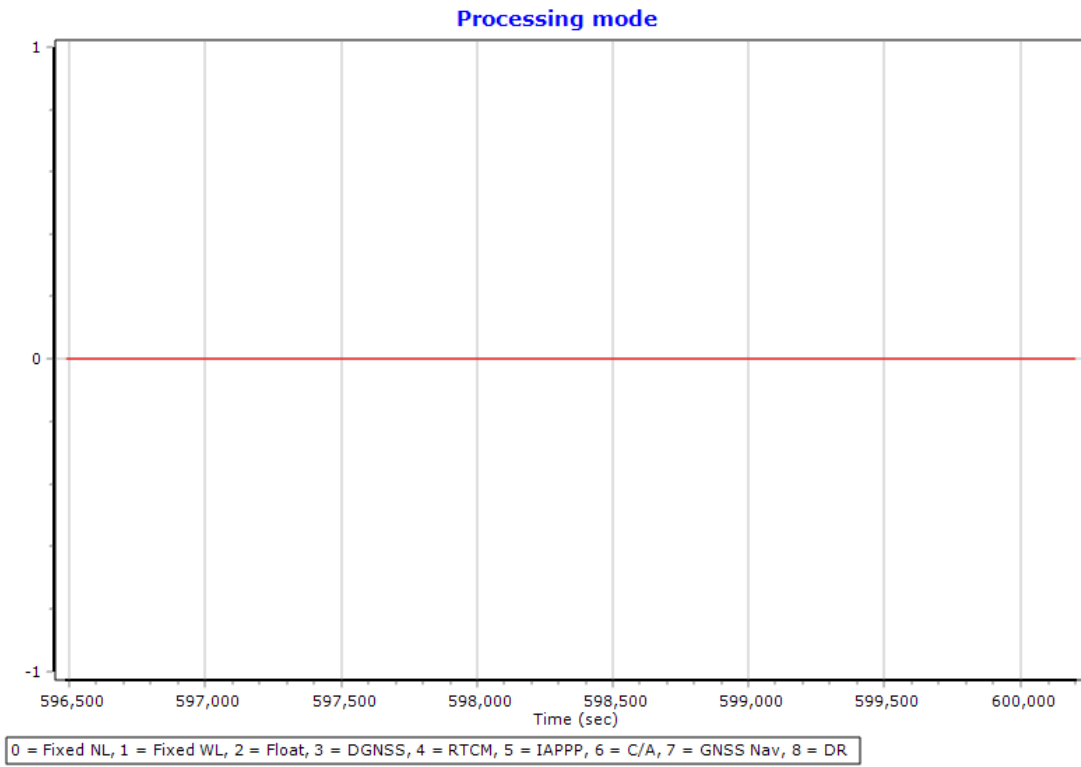
OK Cancel



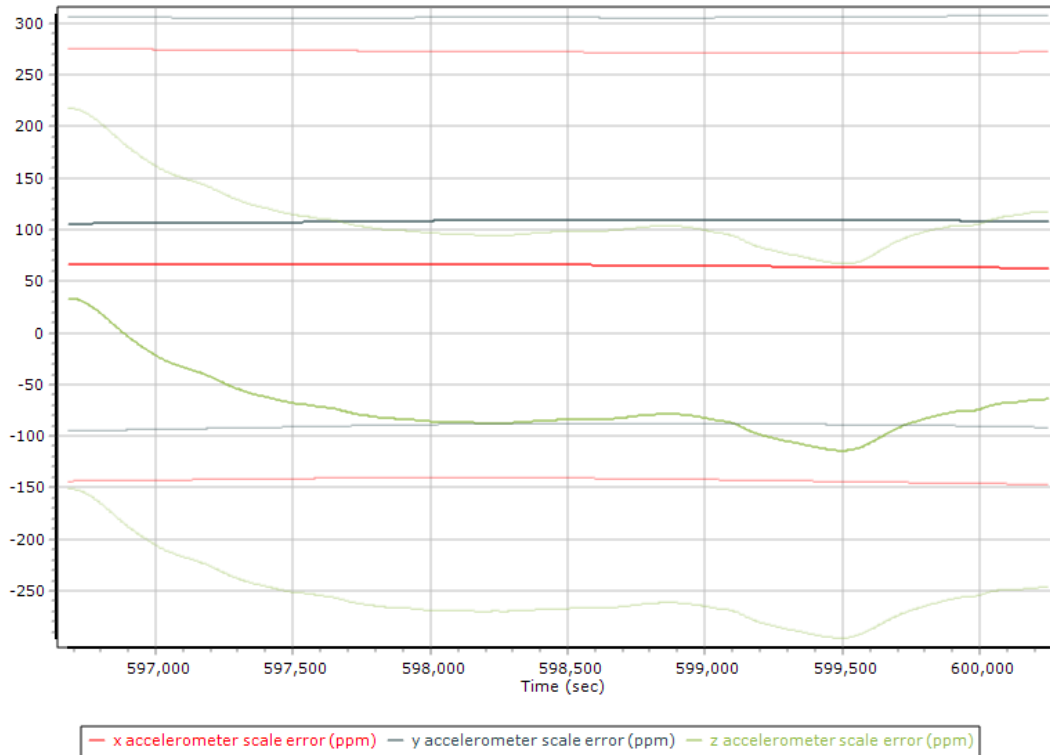
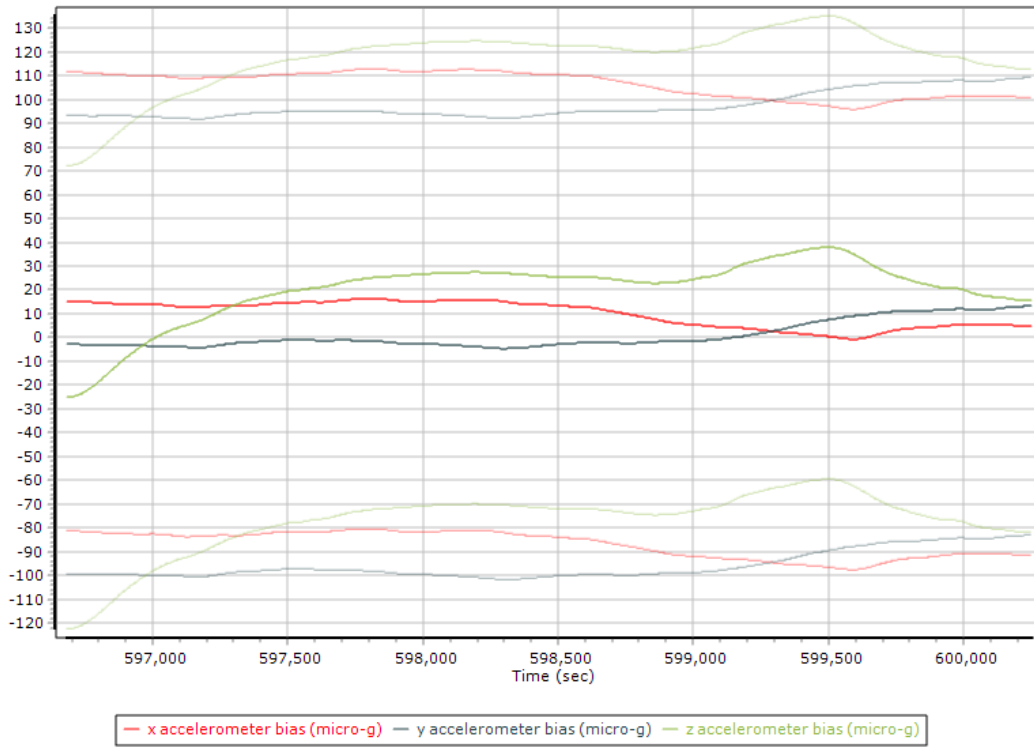


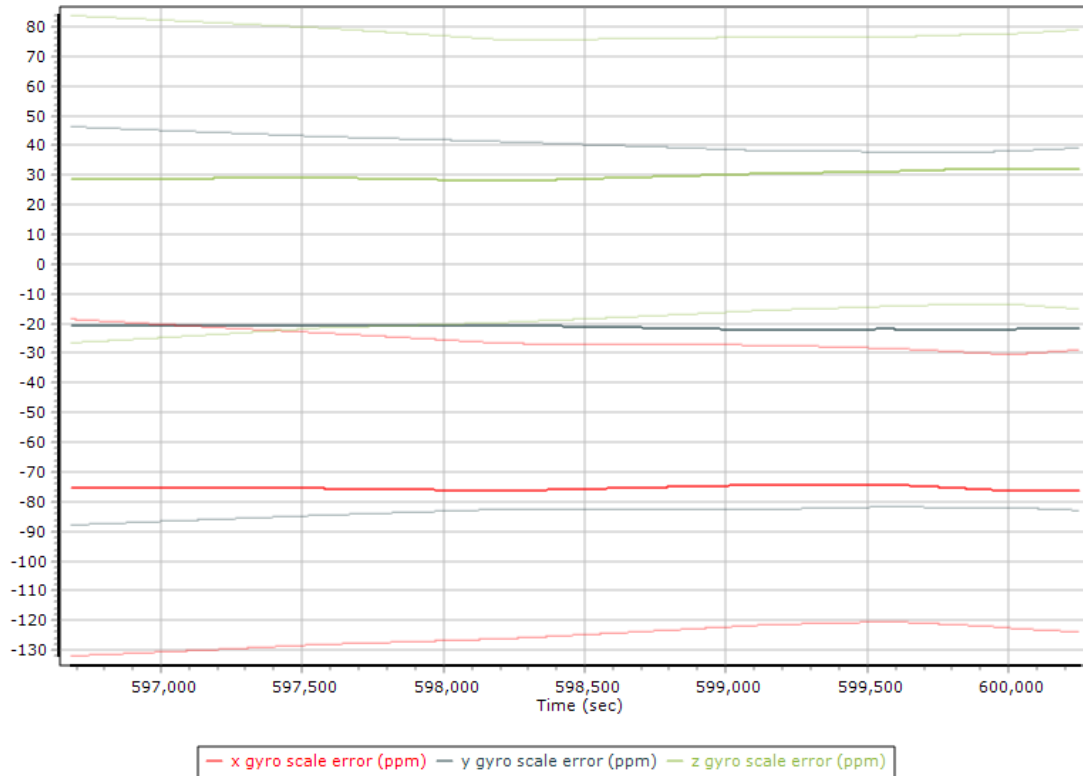
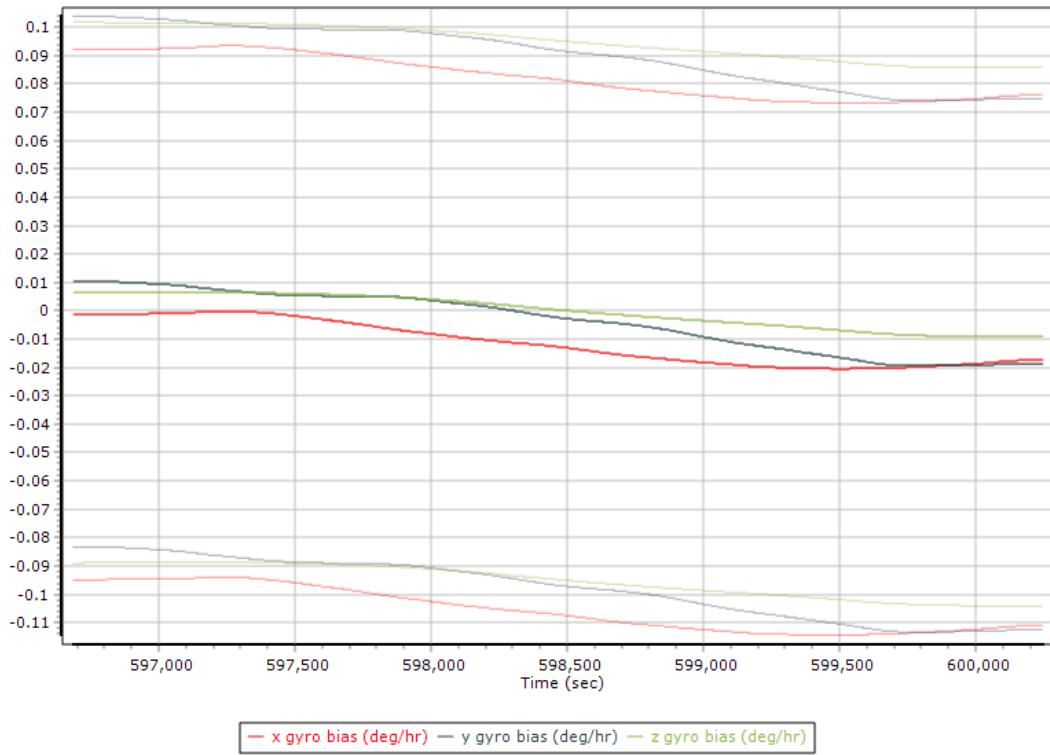




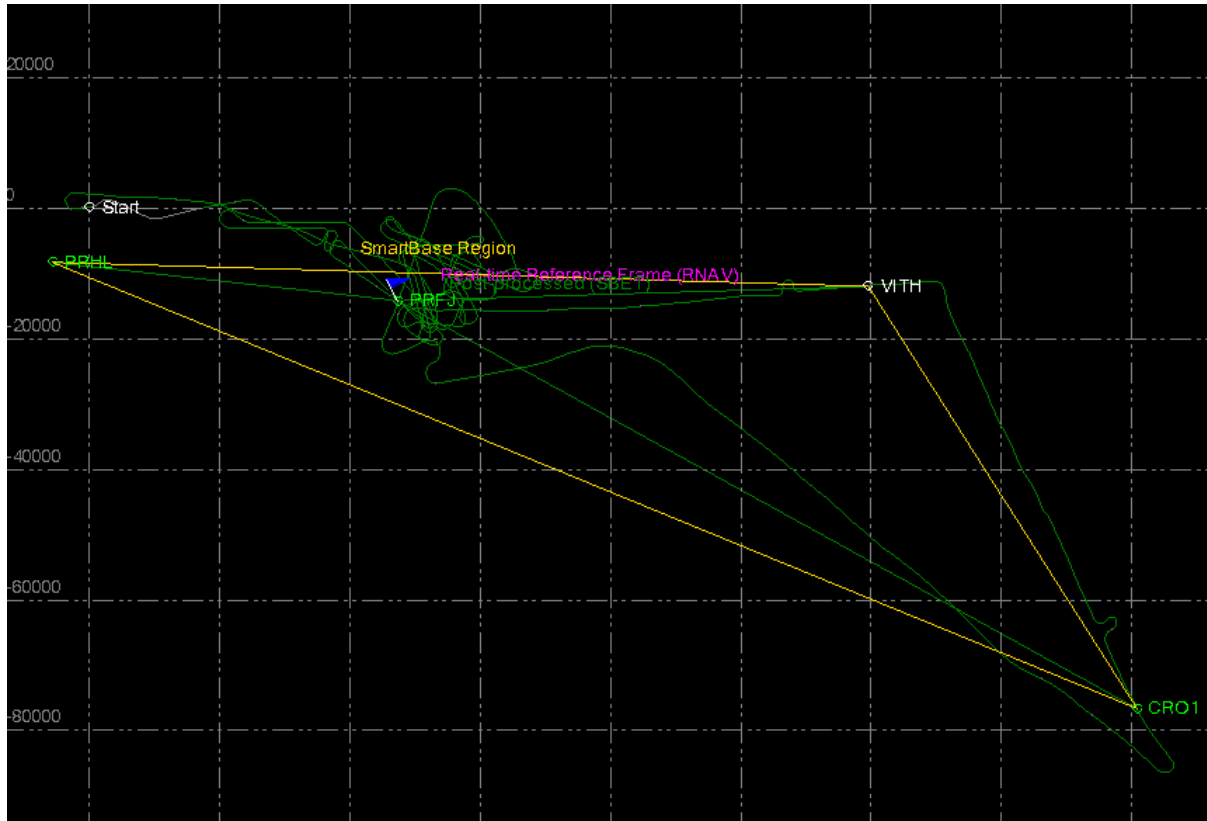


Sensor Errors





AZT18133A



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.

Timing

Start 5/13/2018 5:52:49 PM

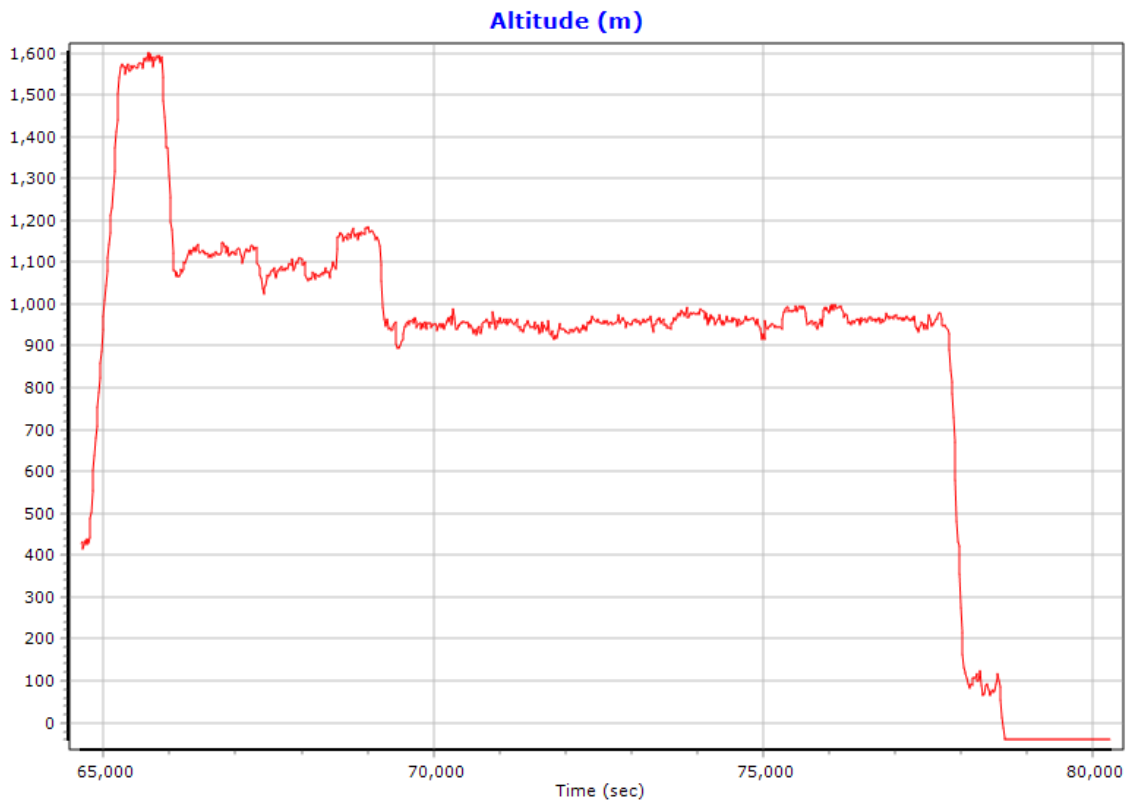
End 5/13/2018 10:18:02 PM

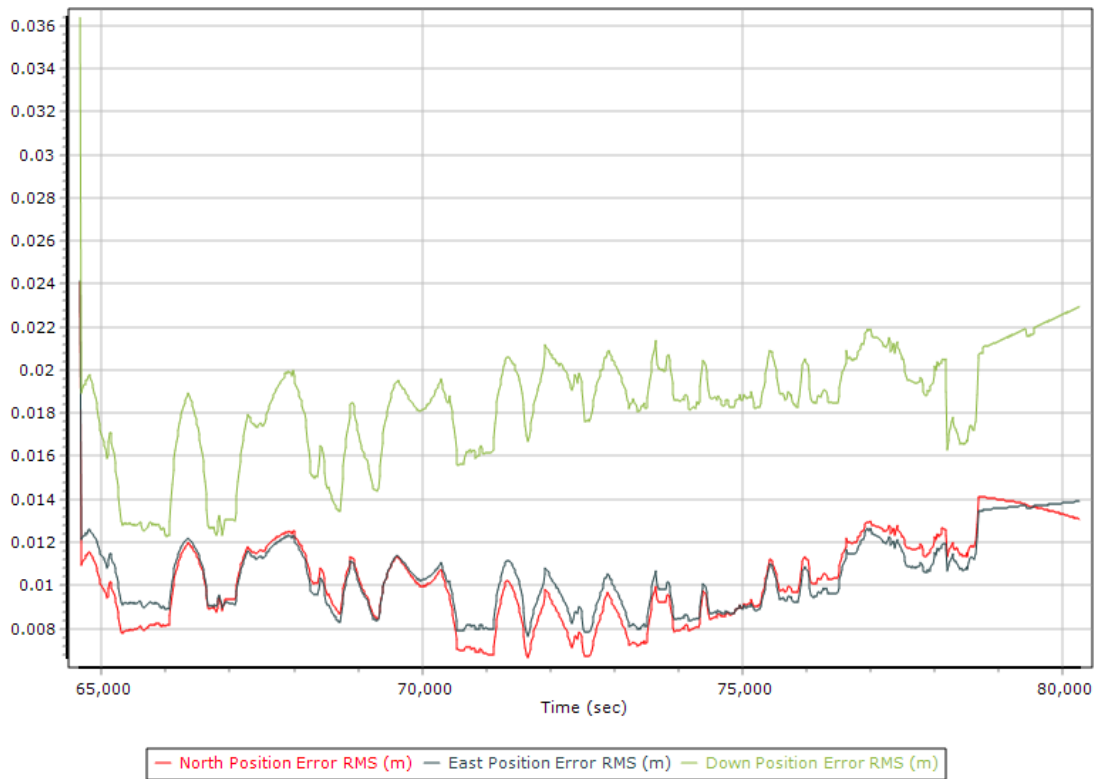
Entire time interval

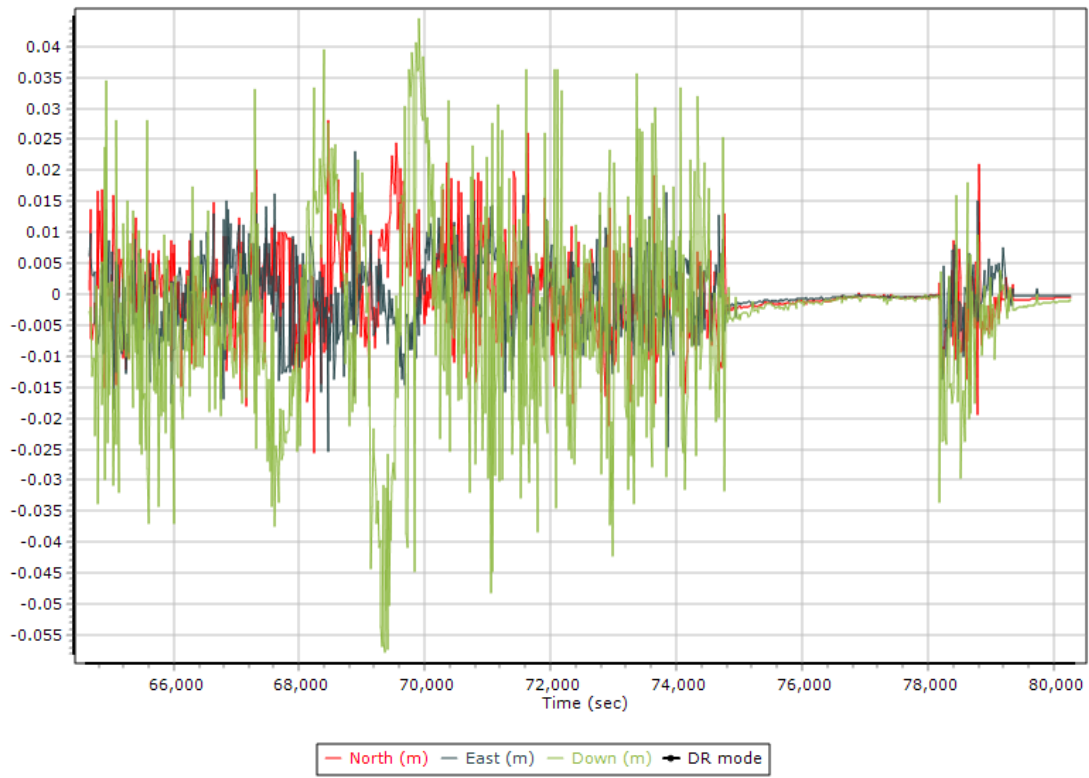
Seconds of start week

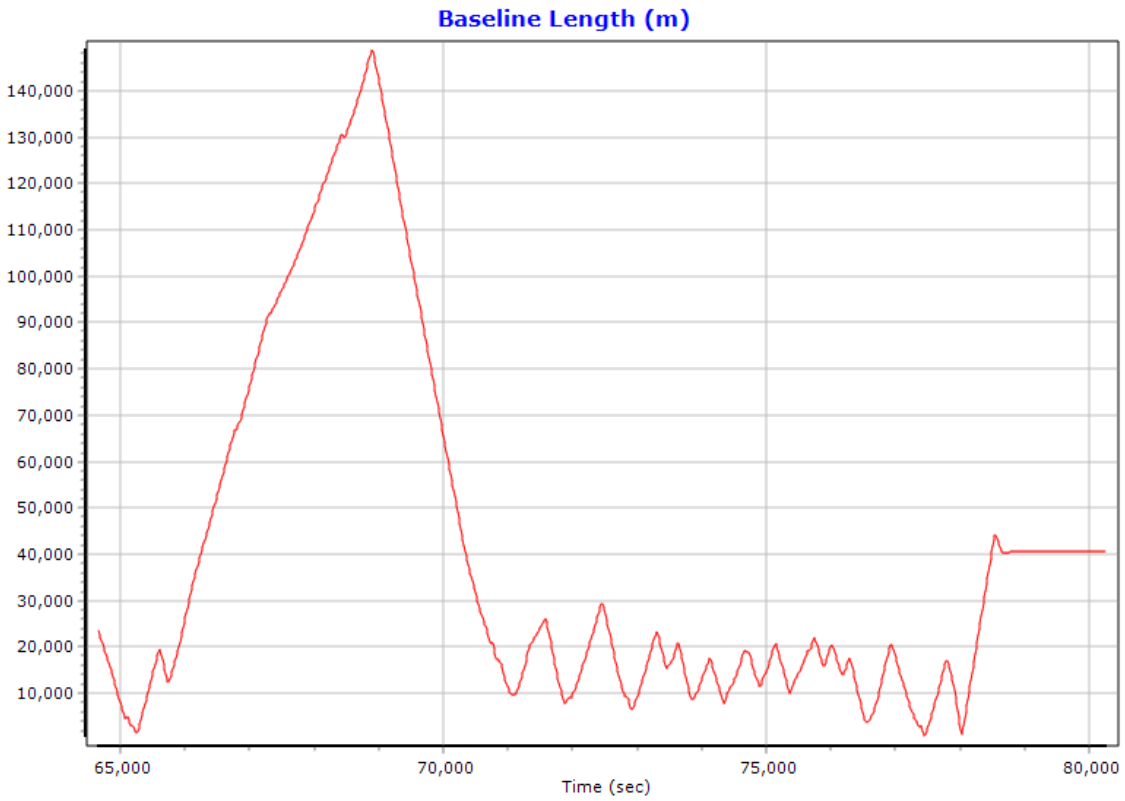
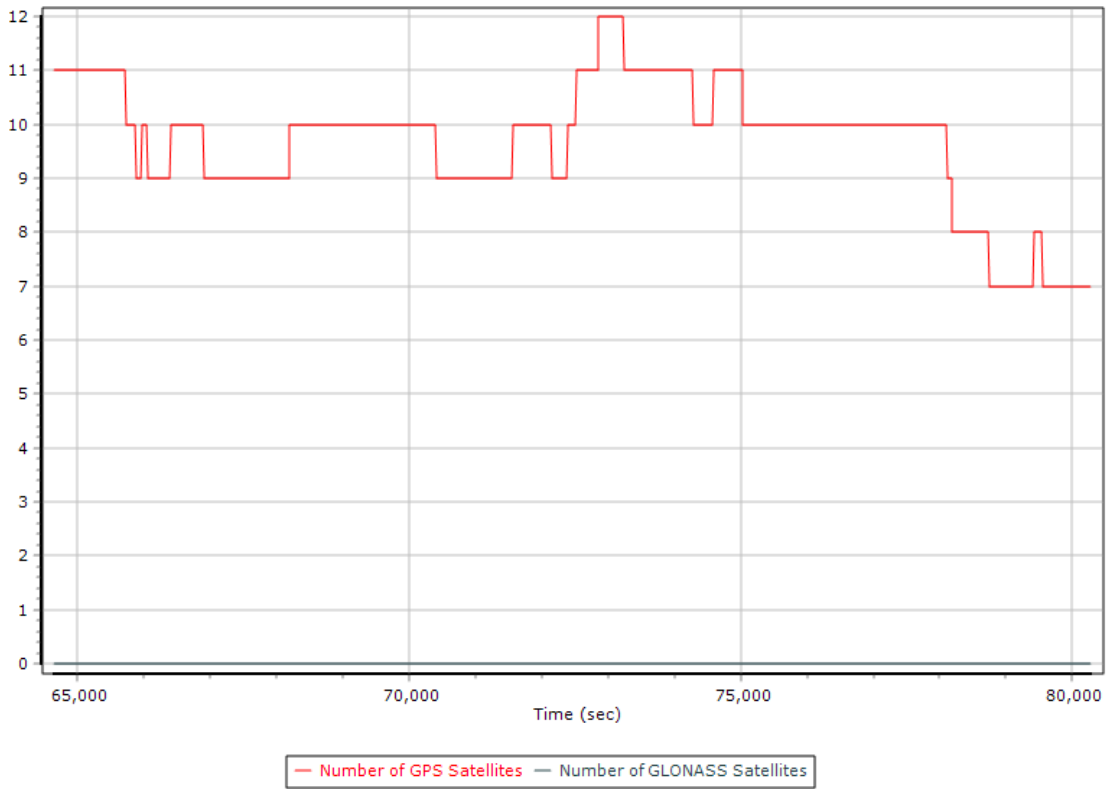
UTC Offset 18.000

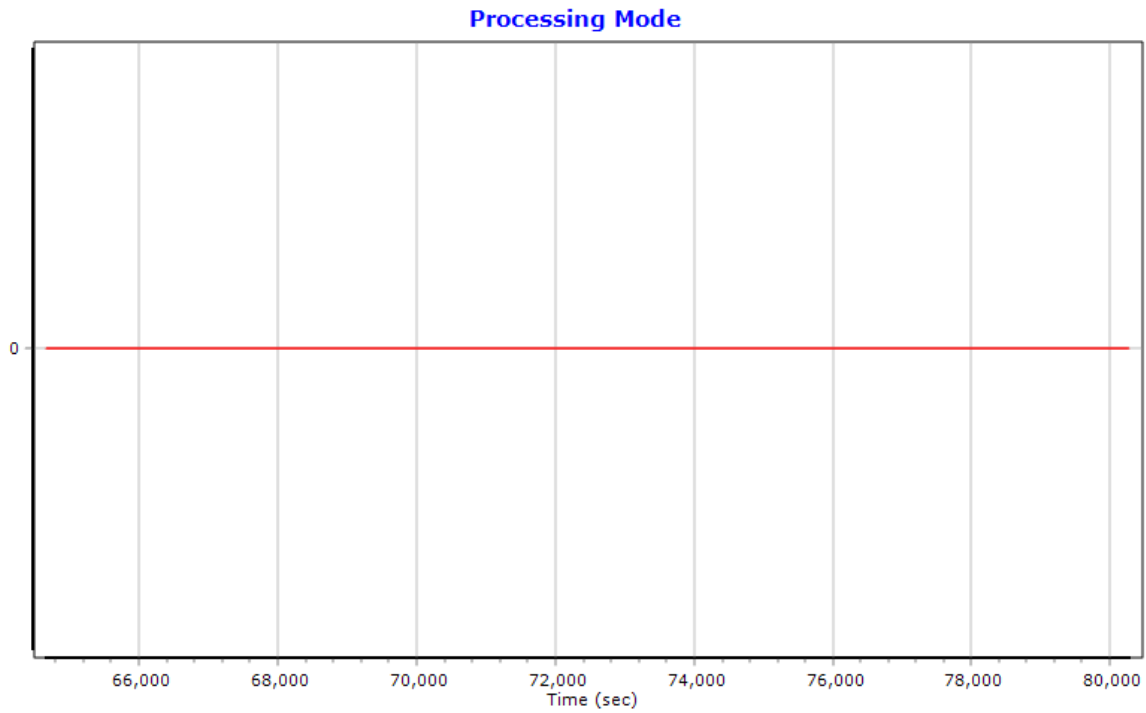
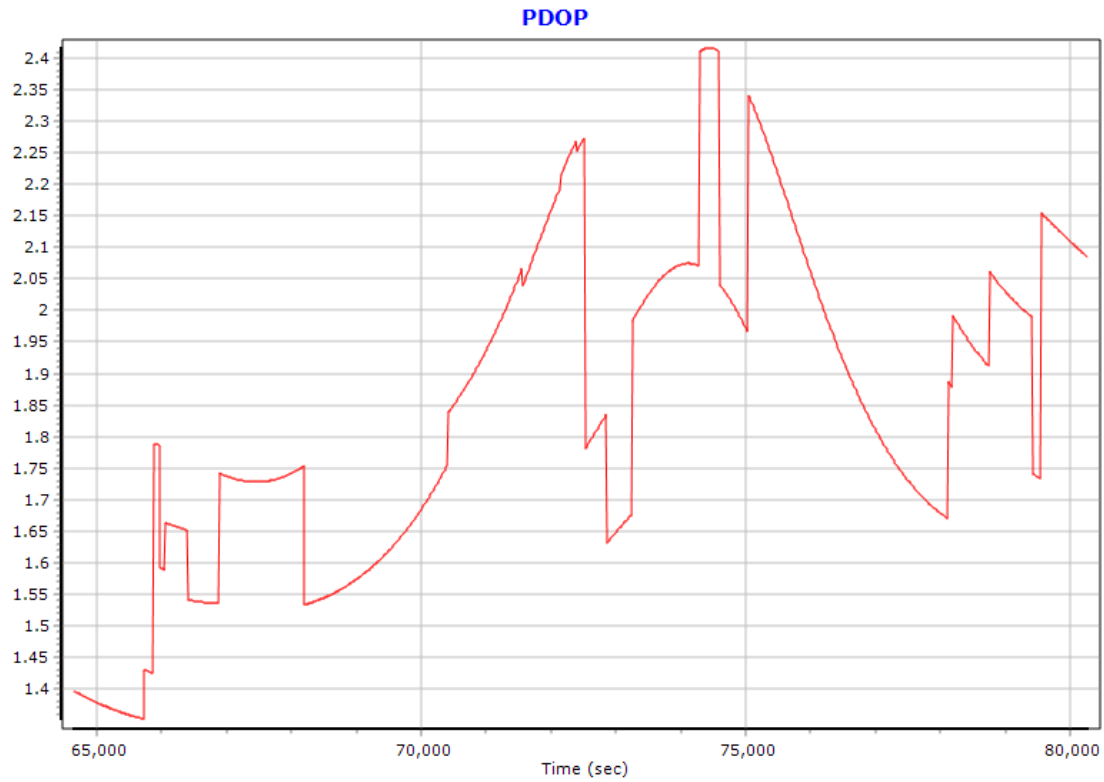
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000







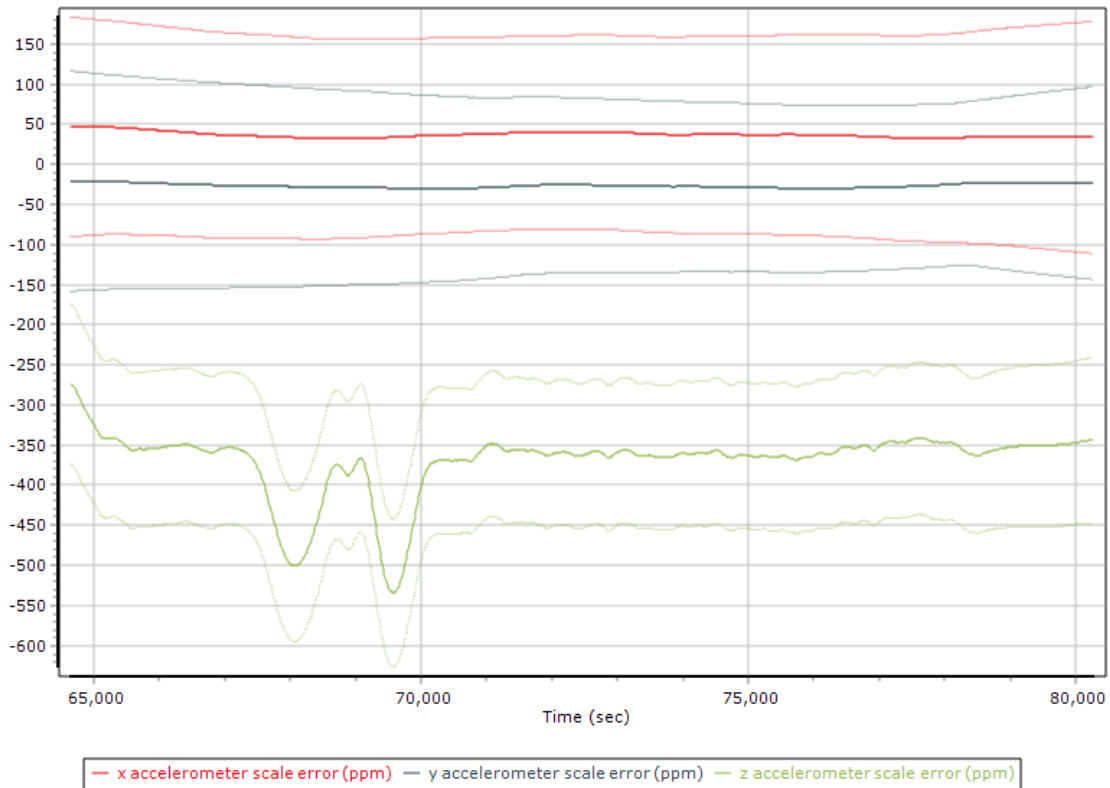
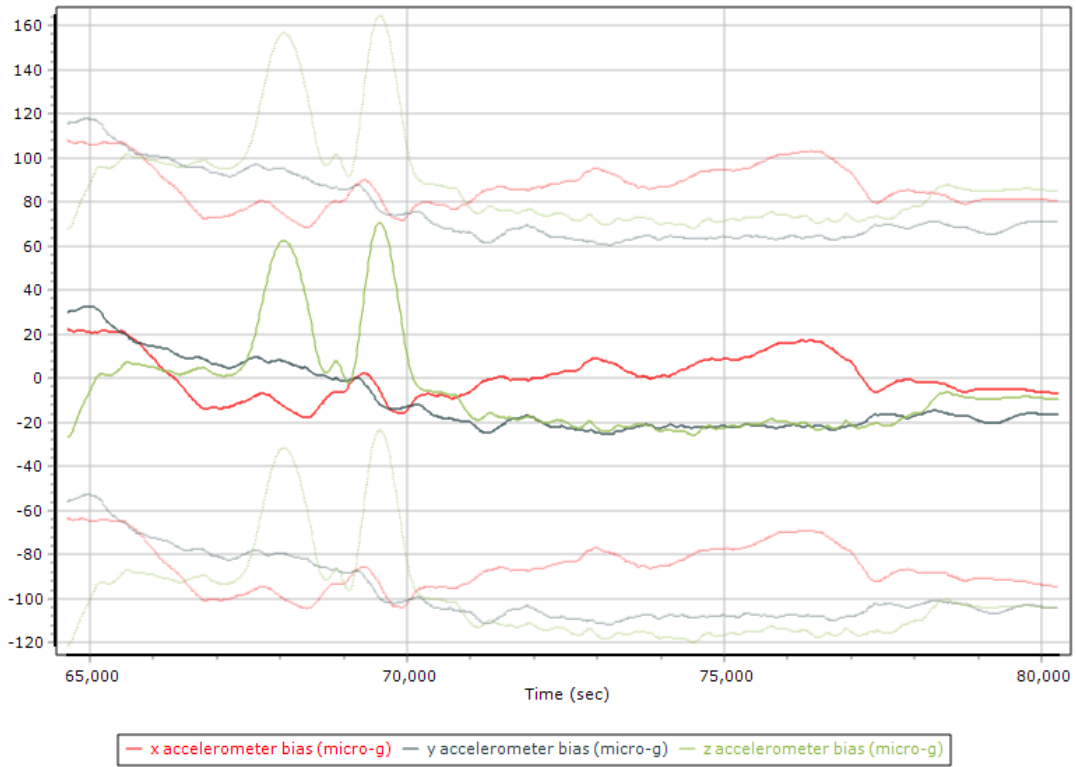


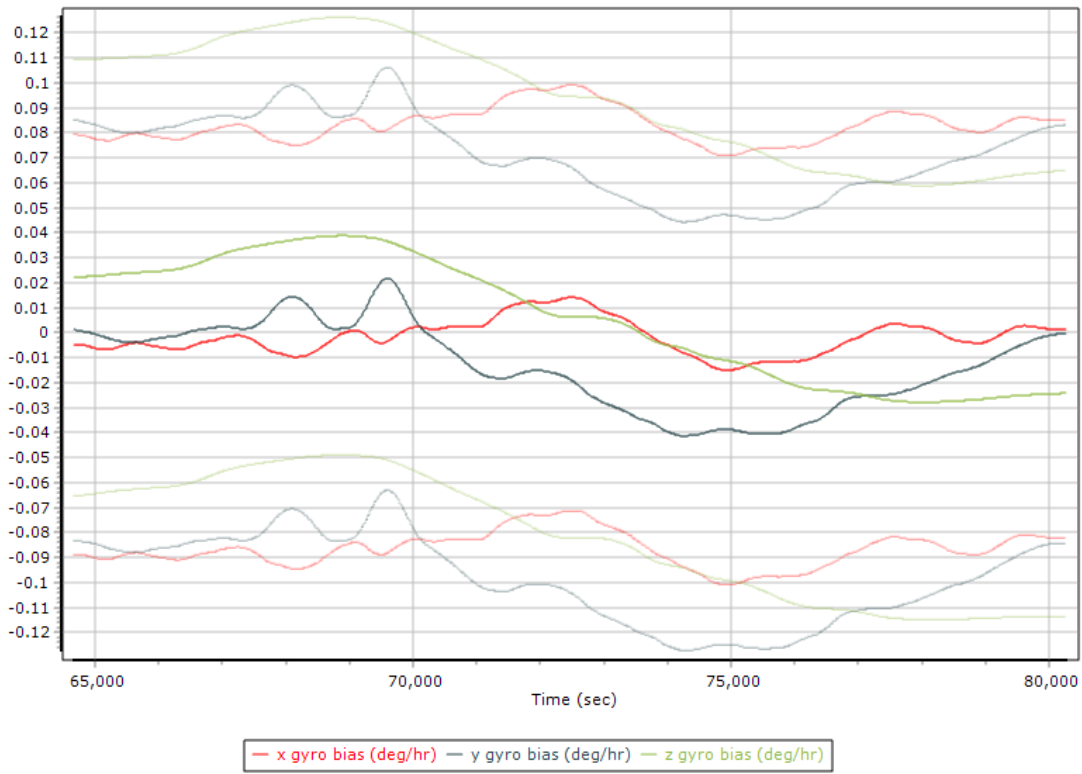


Forward Reverse

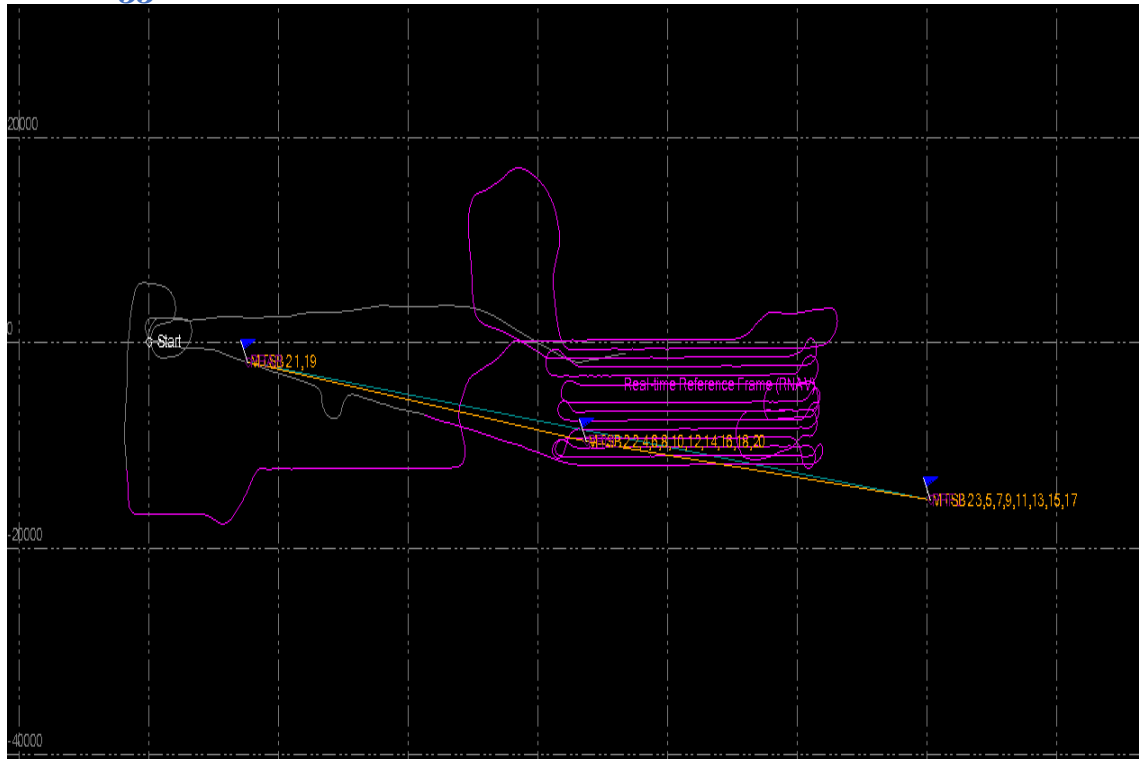
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





AZT18133B



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: <input type="range" value="0.3"/>	
<3cm 10cm 50cm 1m 10m	

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

Timing

Start

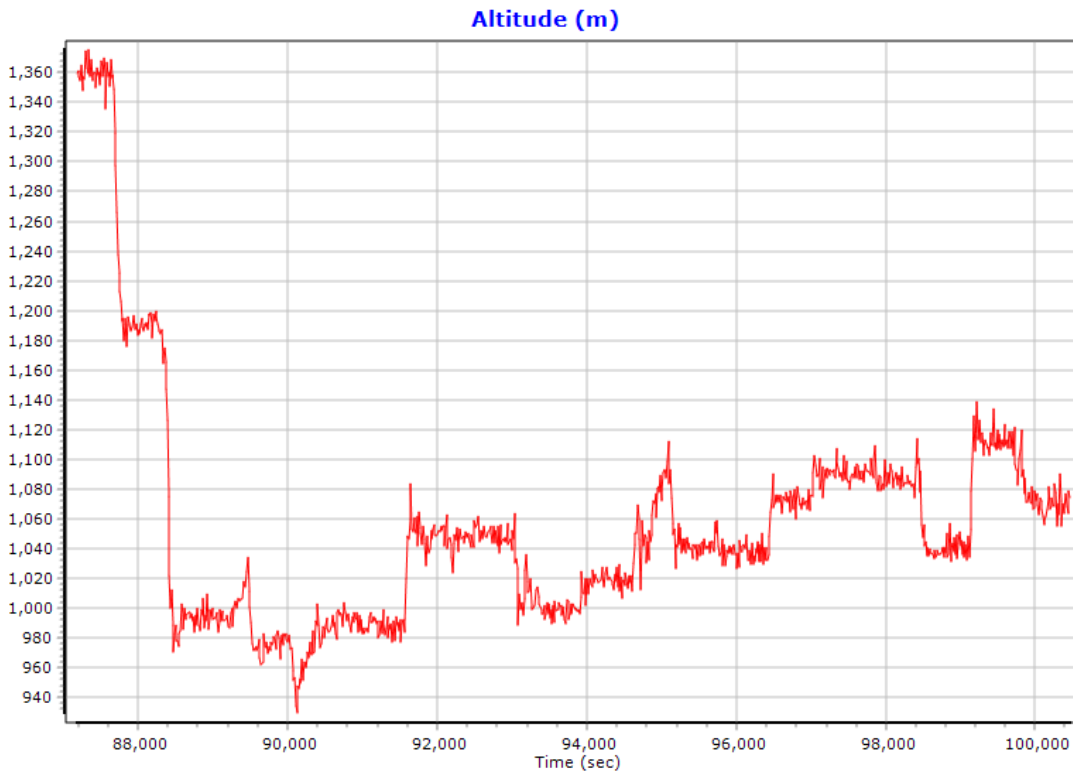
End

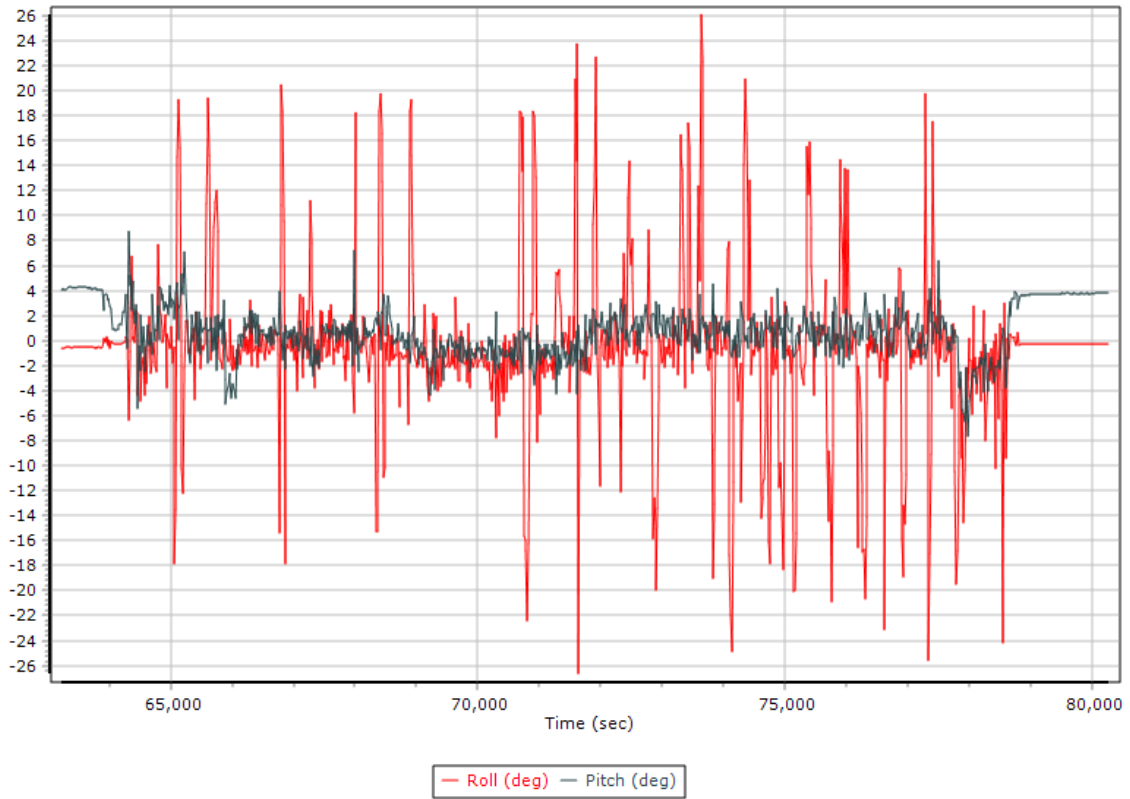
Entire time interval

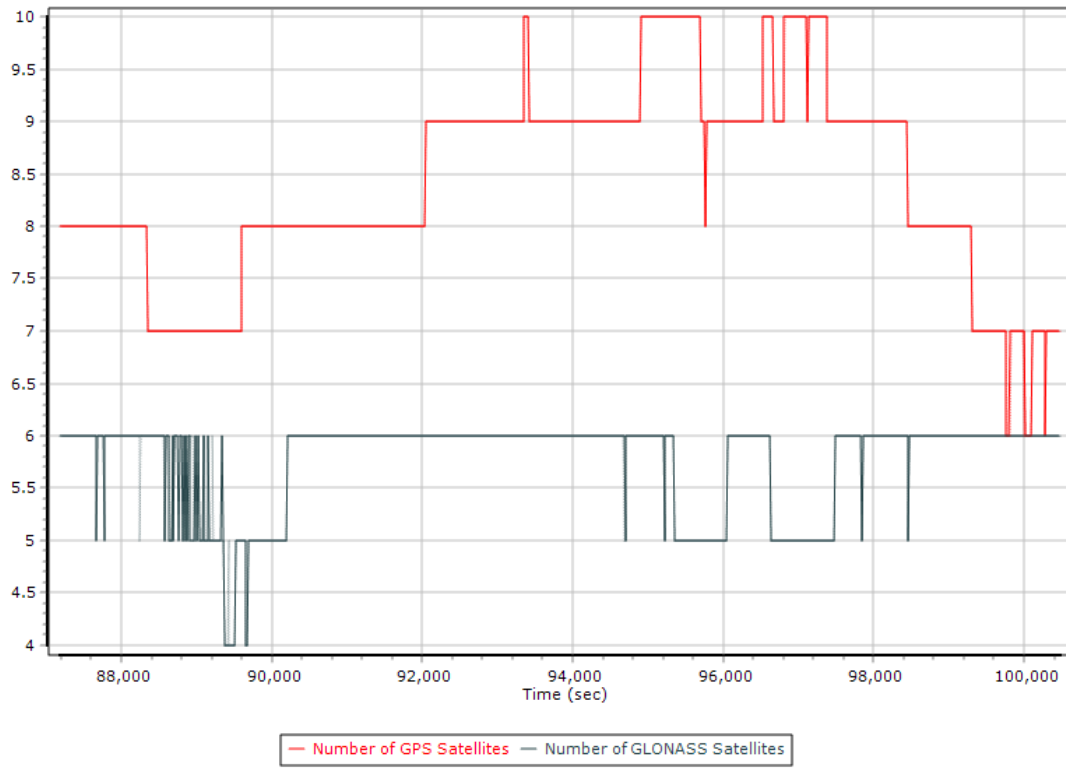
Seconds of start week

UTC Offset

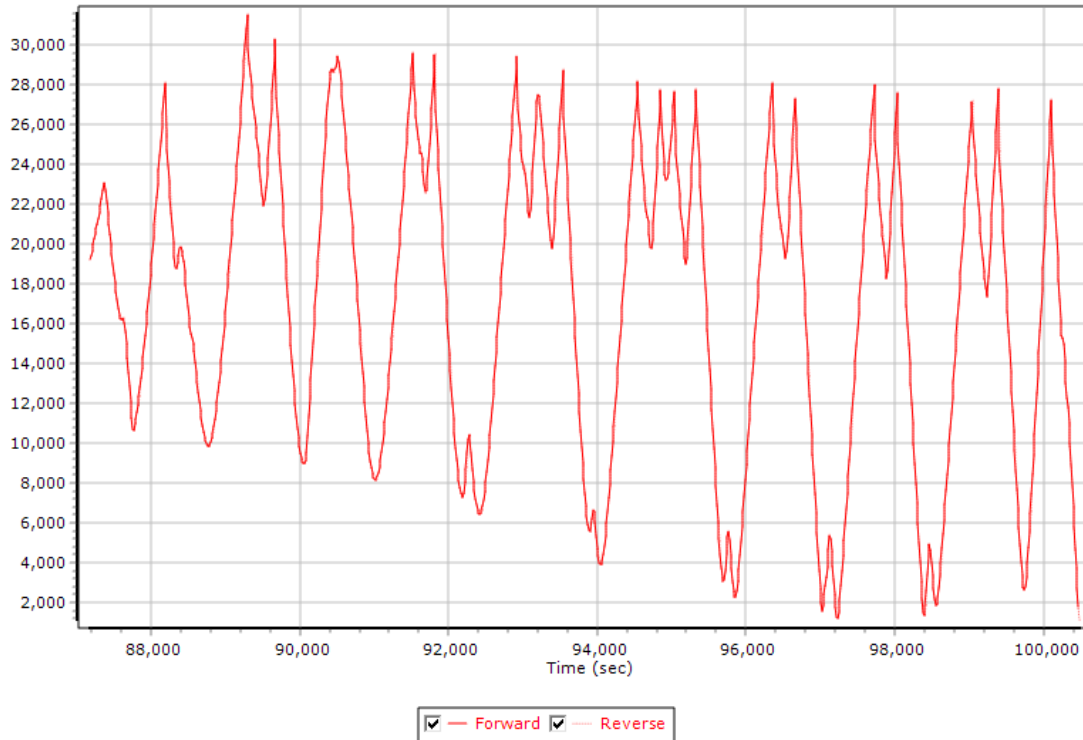
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



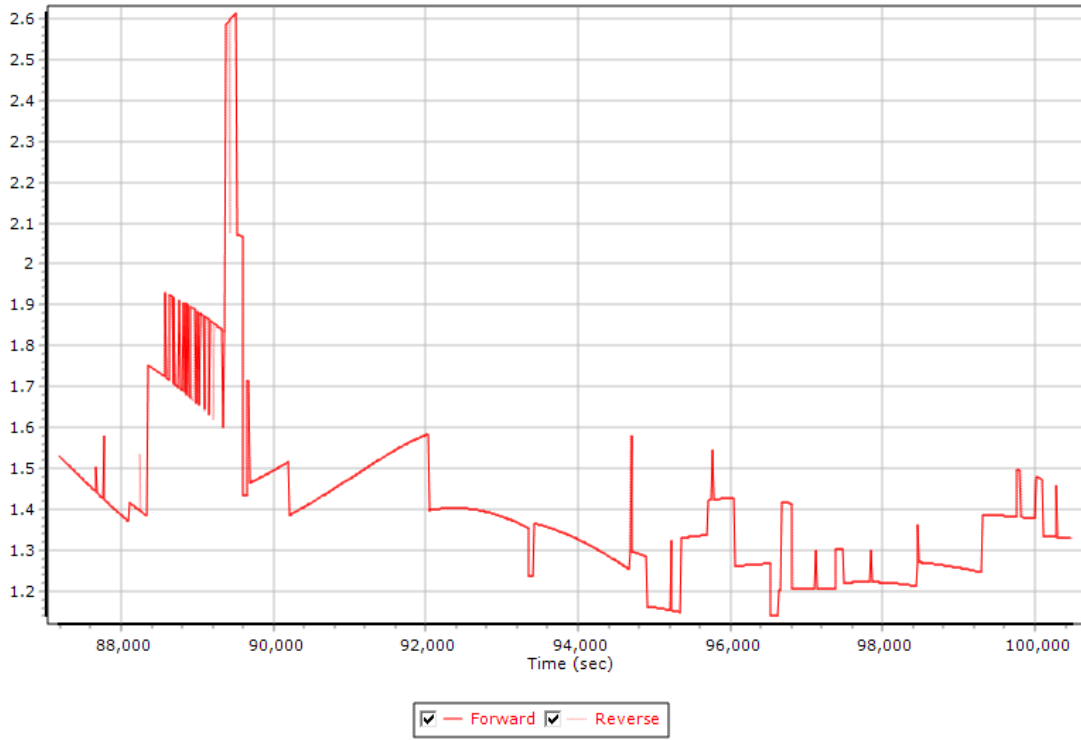




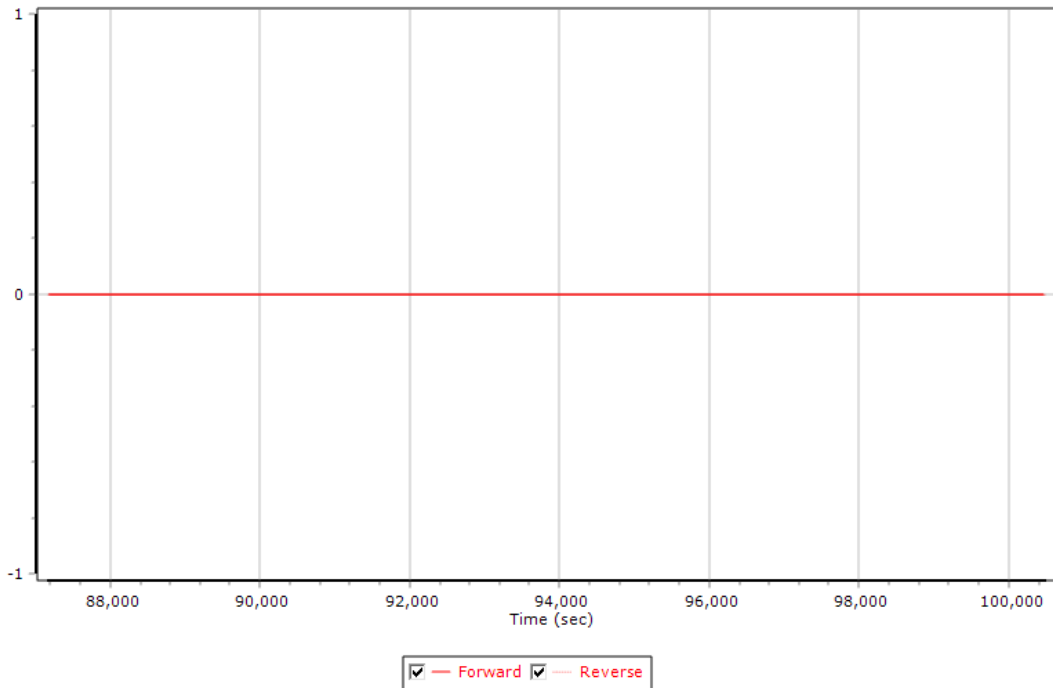
Baseline Length (m)



PDOP

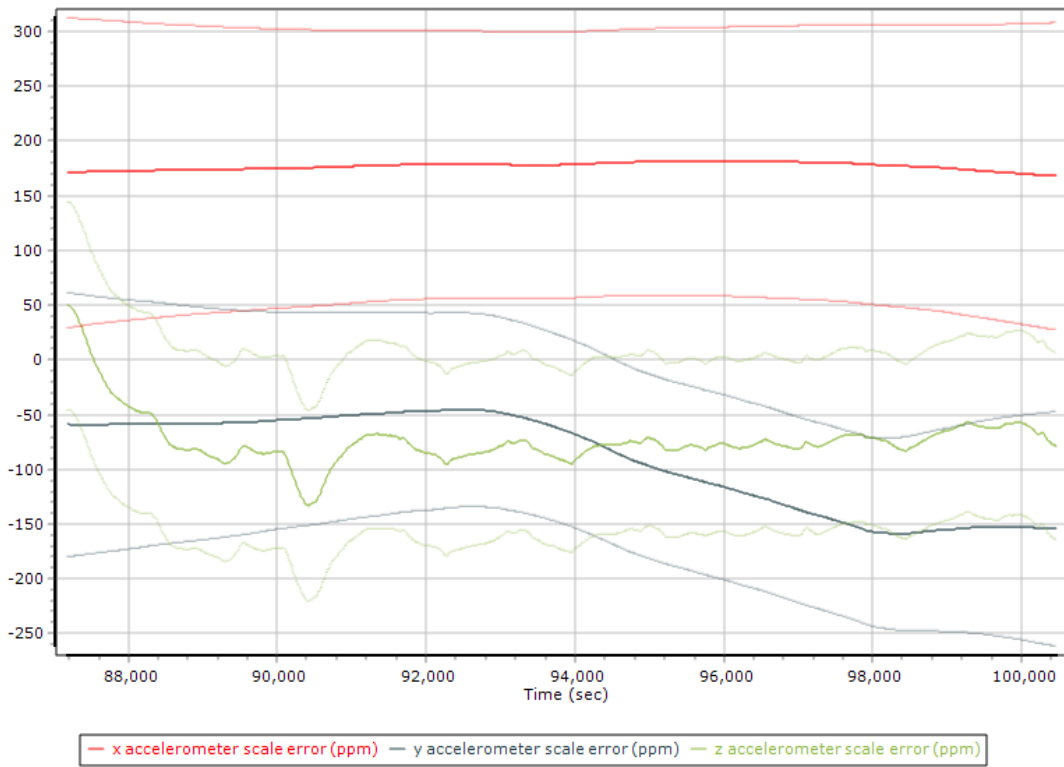
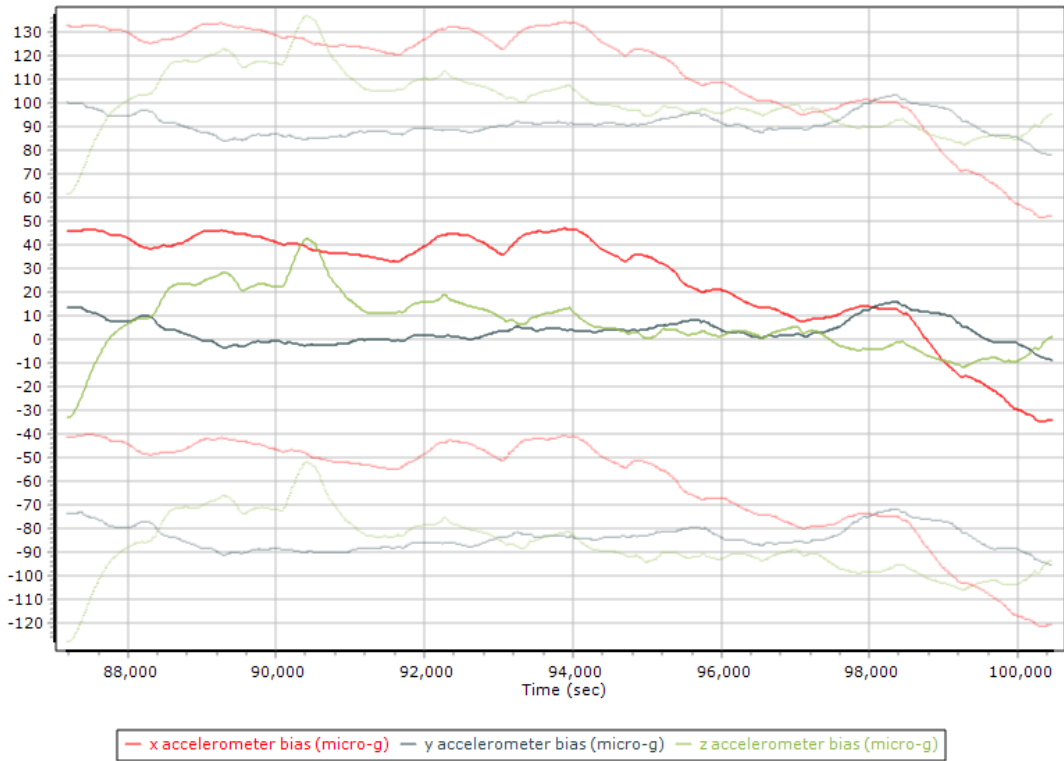


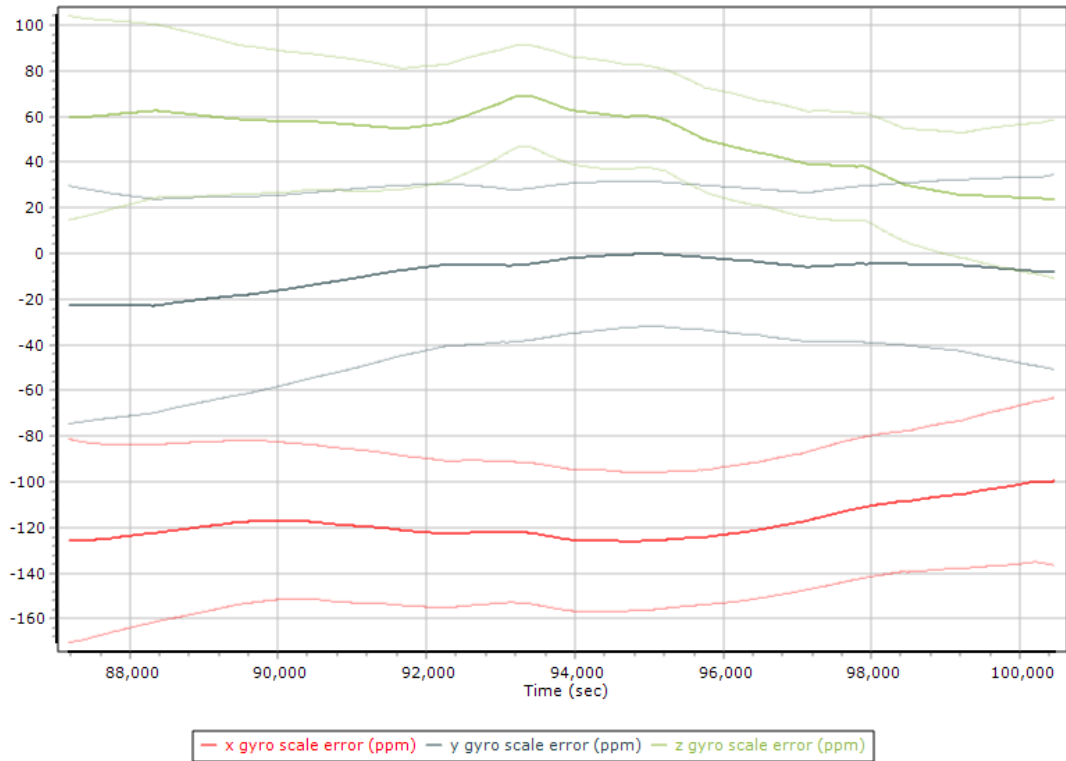
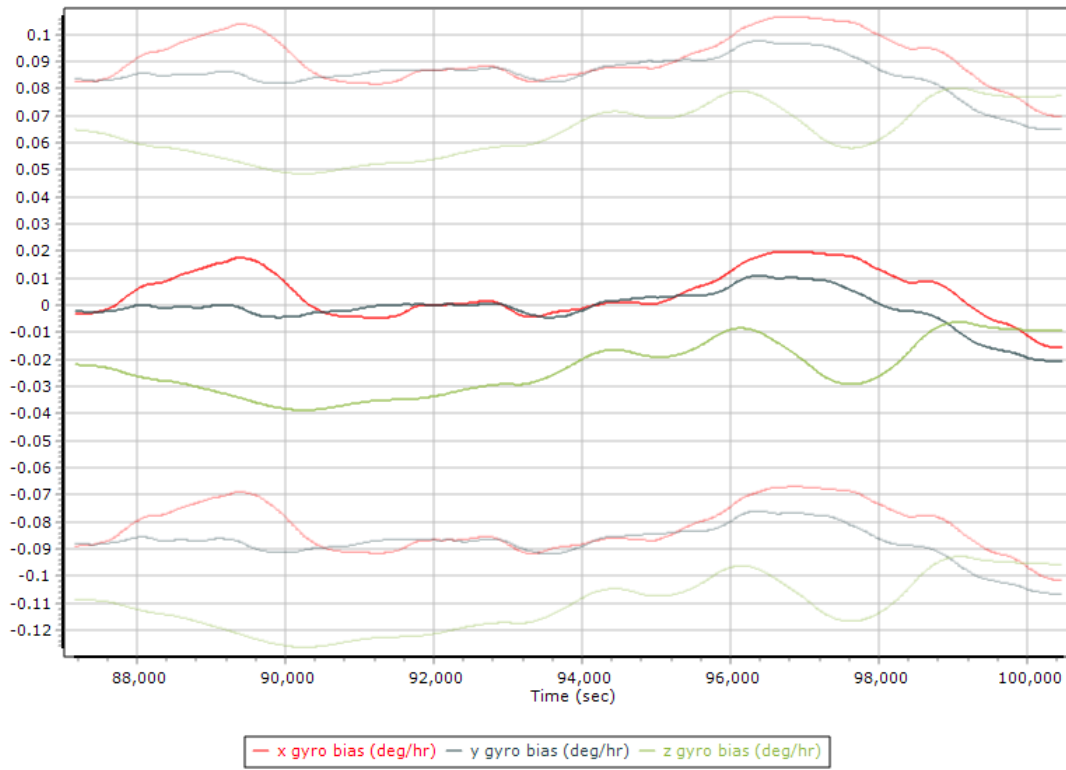
Processing mode



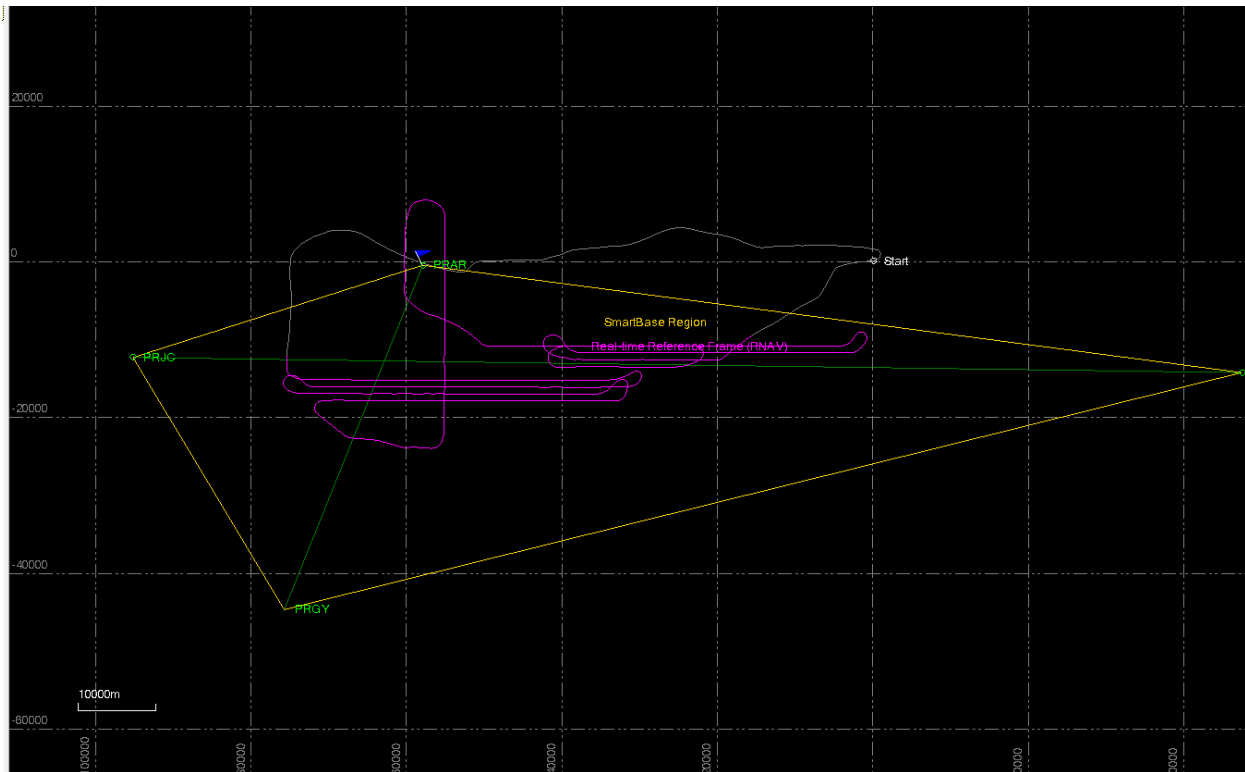
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





AZT18134A



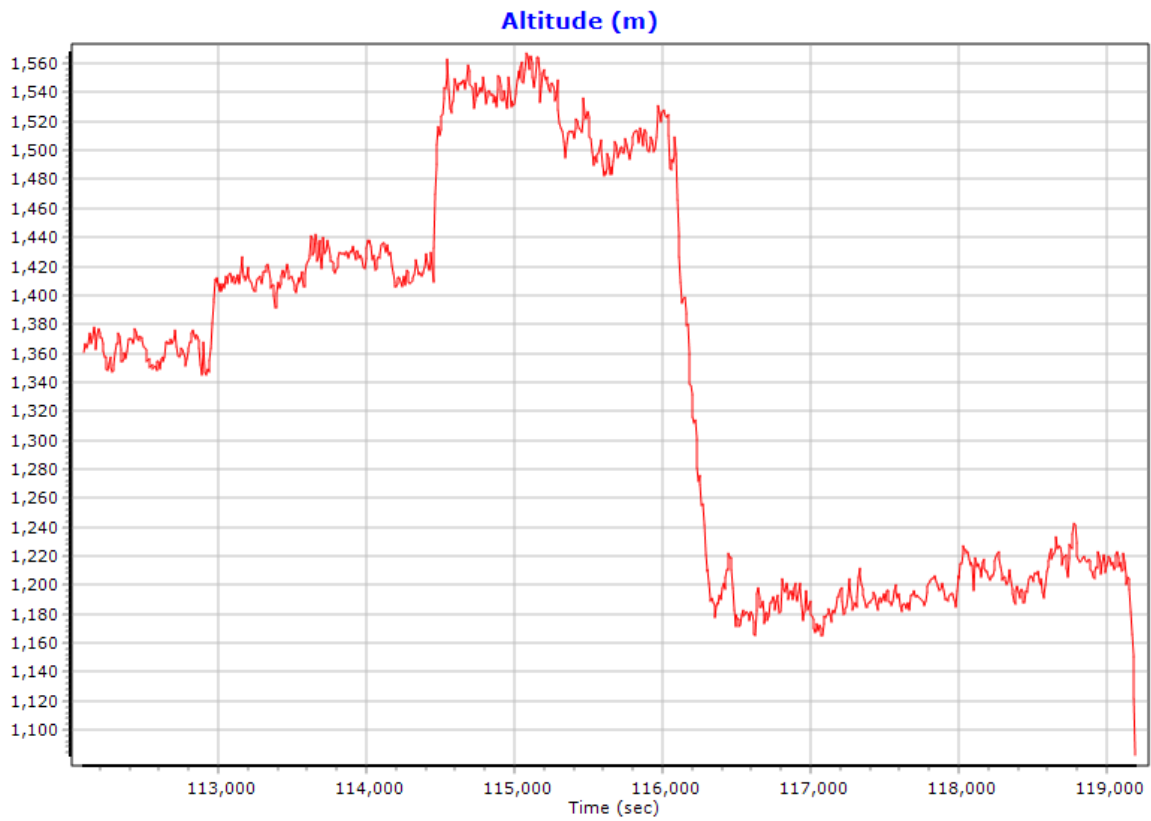
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	-0.034 m	X	0.000 deg
Y	-0.010 m	Y	0.000 deg
Z	-0.352 m	Z	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm		Aircraft to Stabilized Mount Mounting Angles	
X	-0.049 m	X	0.000 deg
Y	0.003 m	Y	0.000 deg
Z	-1.230 m	Z	0.000 deg
Standard Deviation			
	<3cm 10cm 50cm 1m 10m		

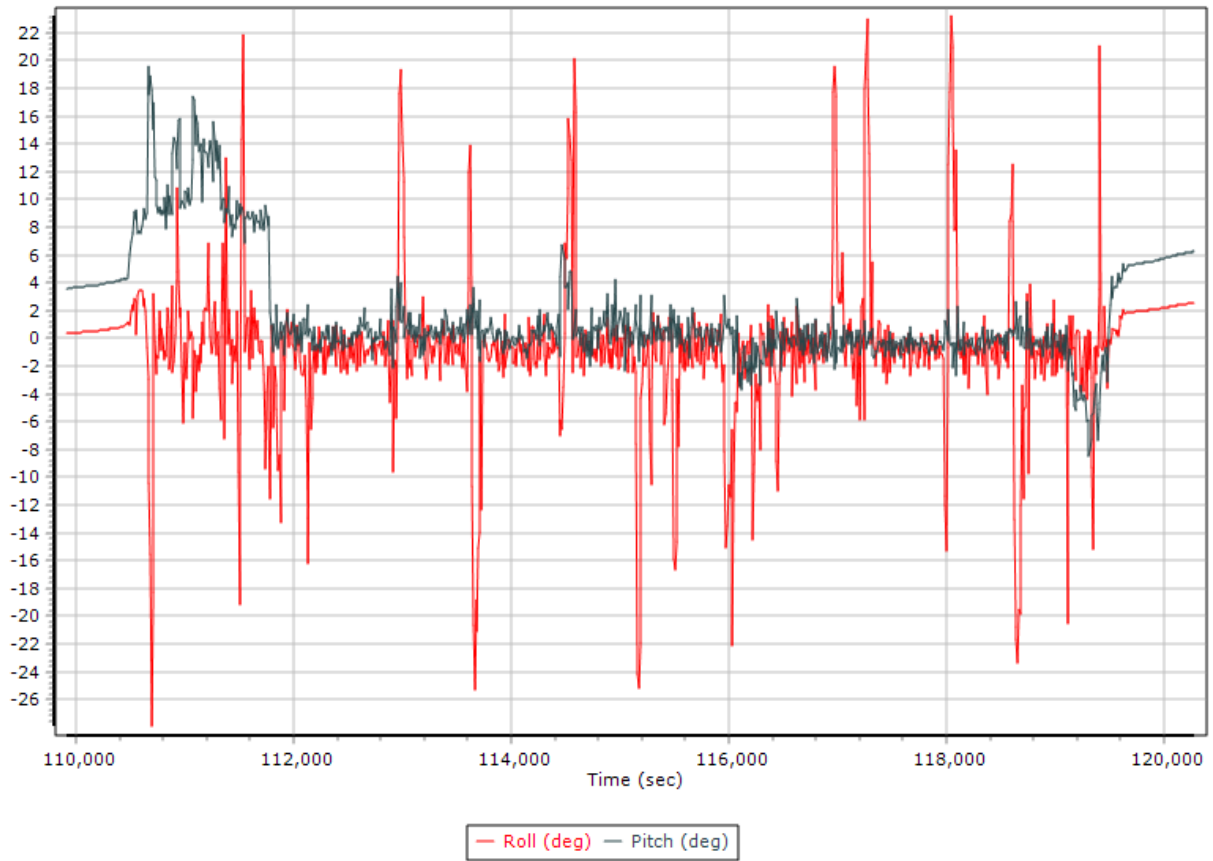
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

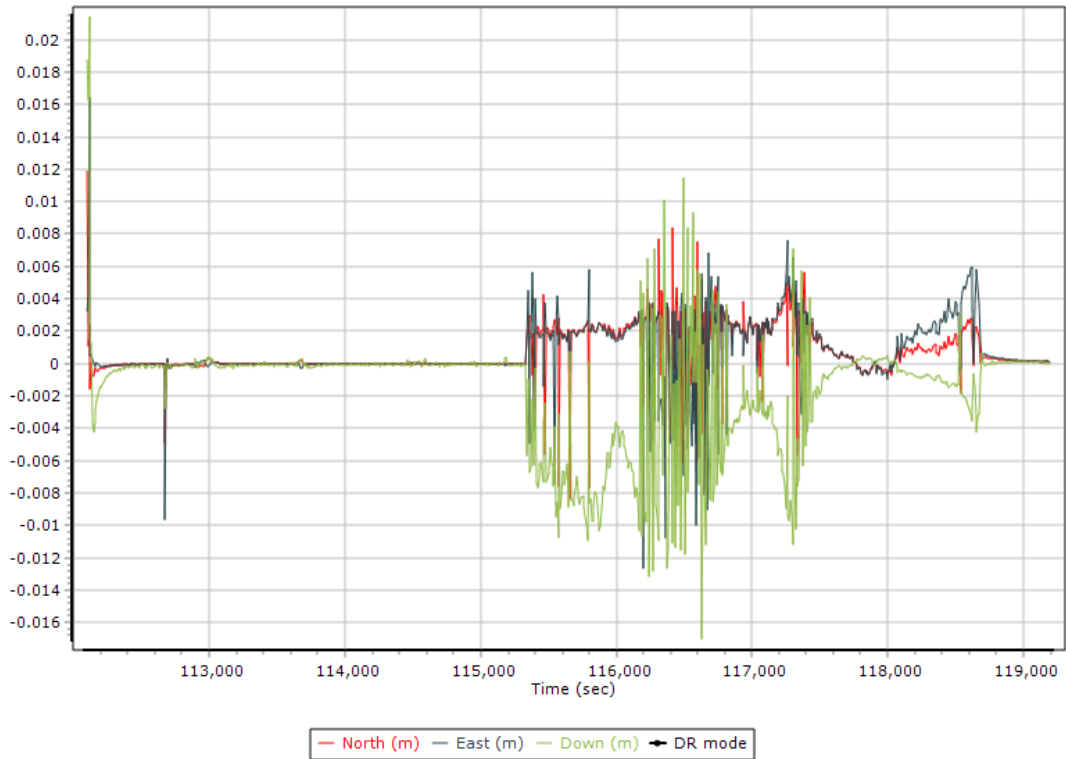
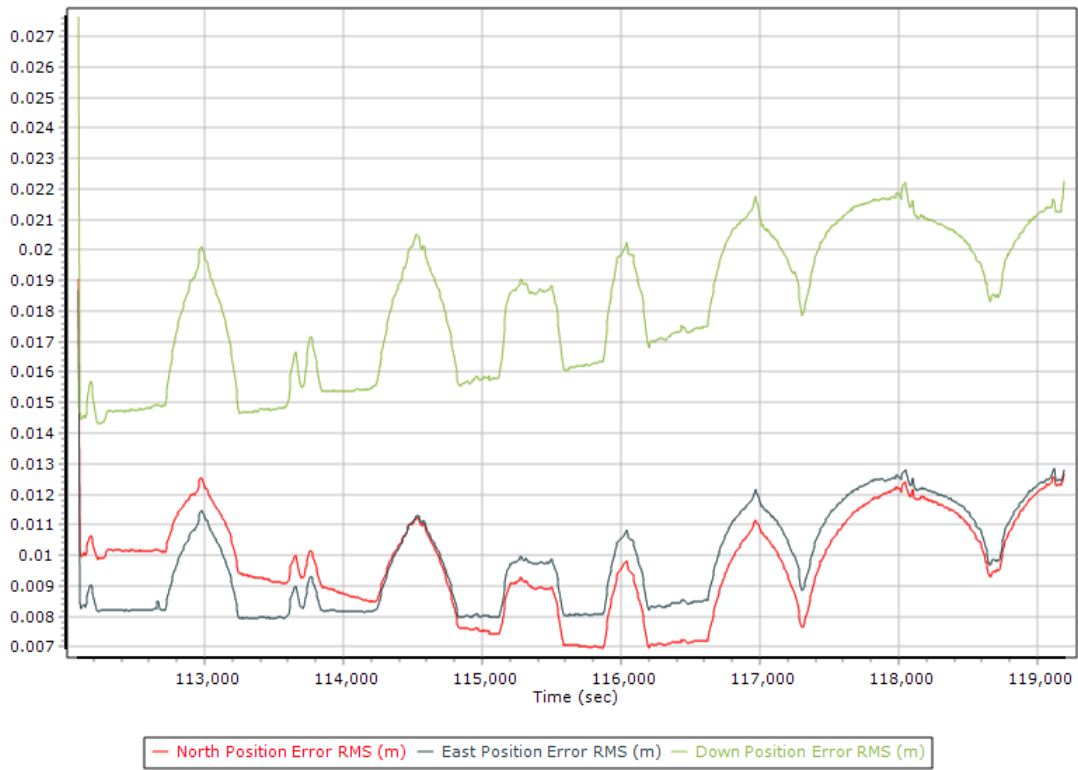
Timing

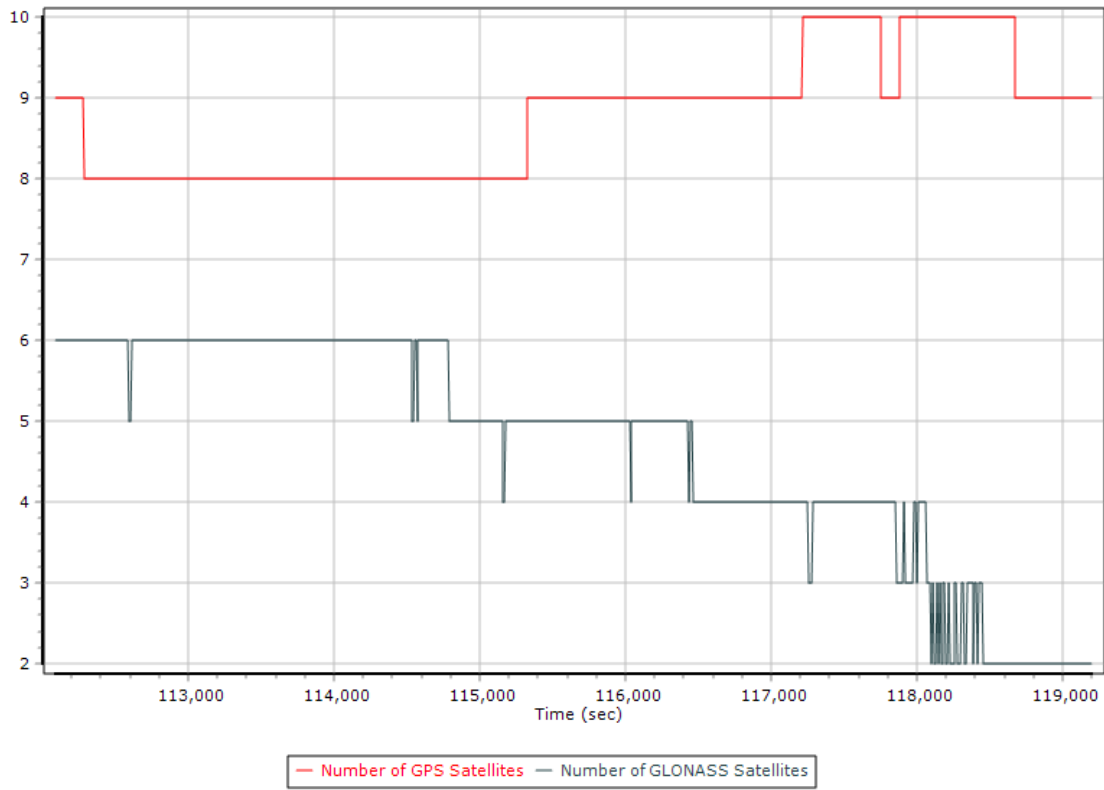
Start	112091.861	Data	Incr. (sec)
End	119200.515	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset

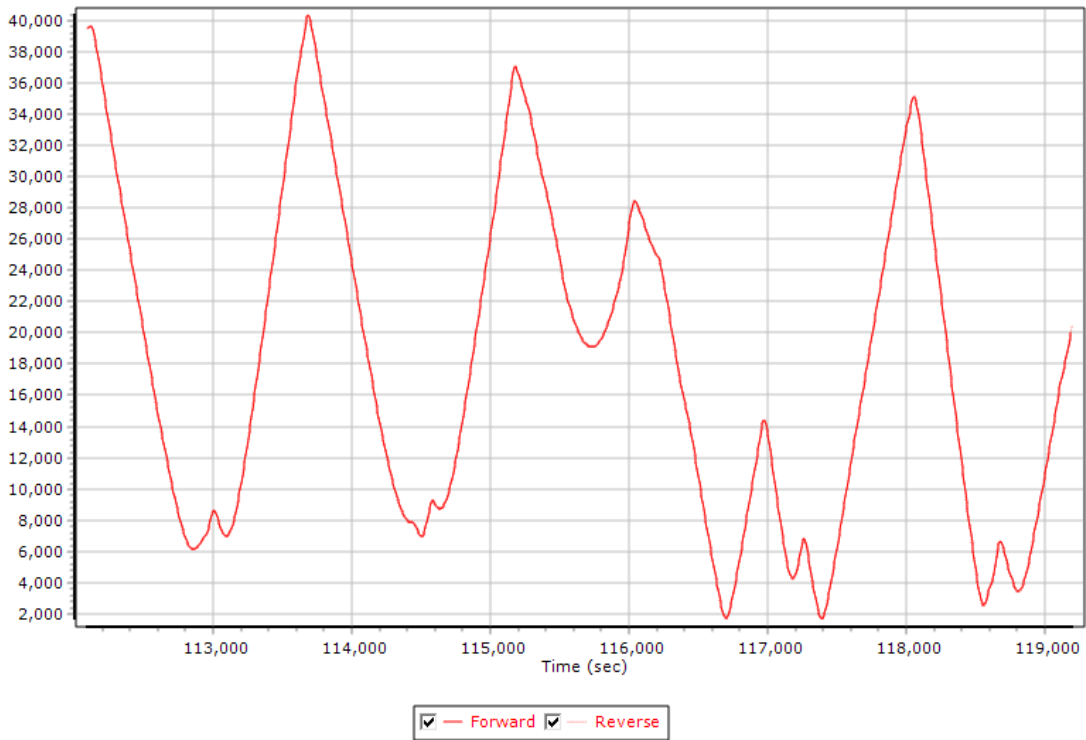




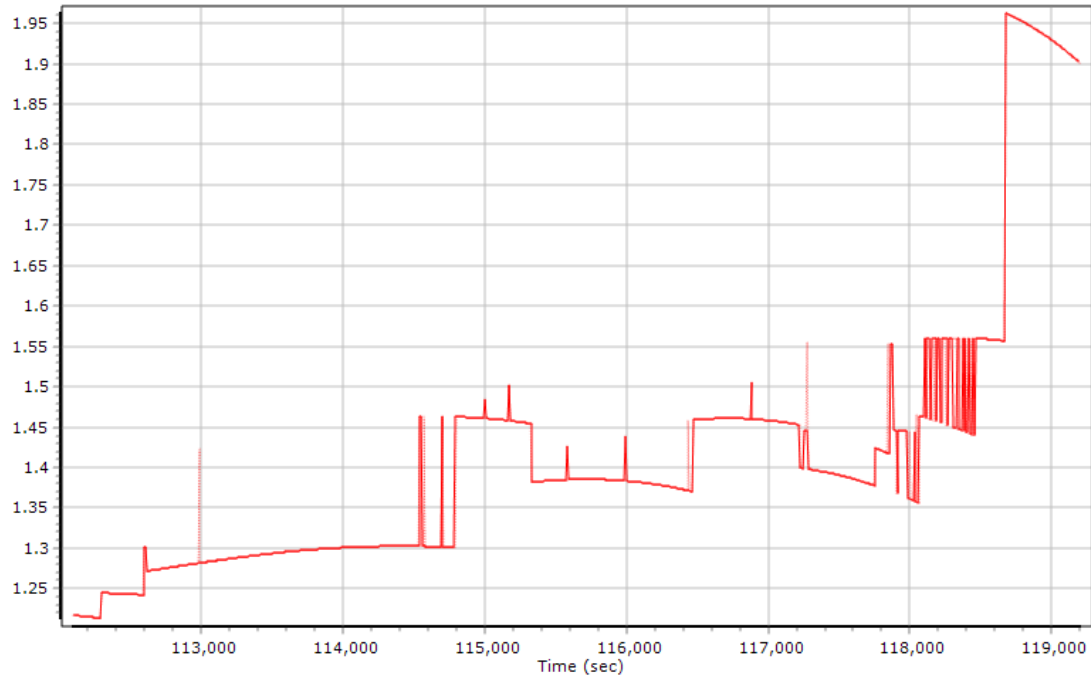




Baseline Length (m)

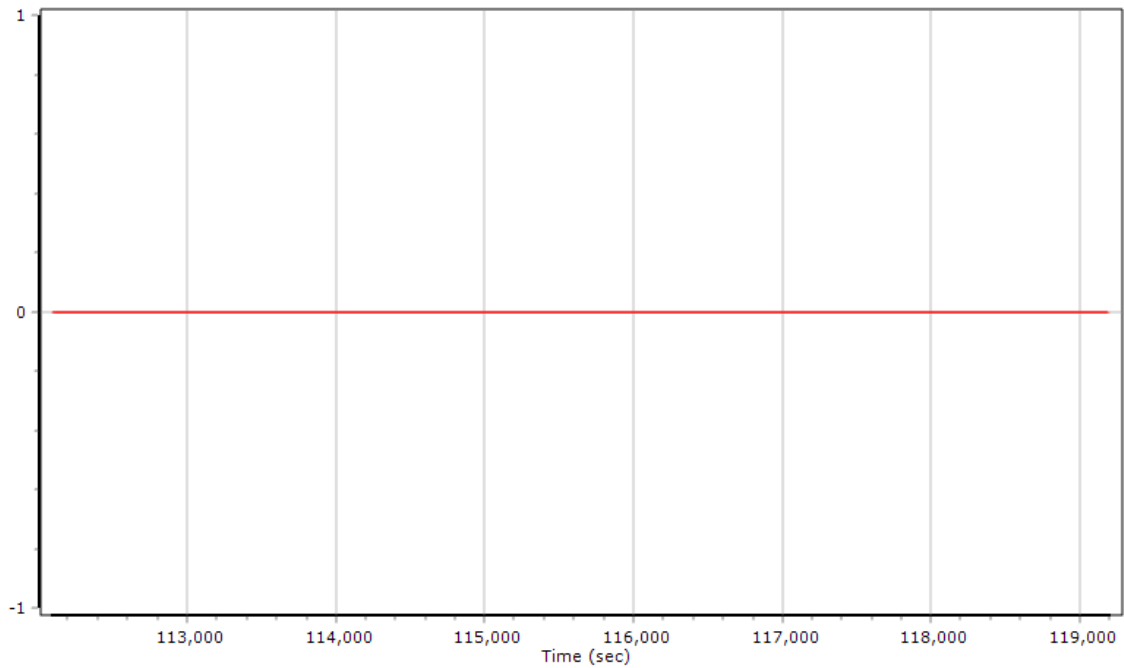


PDOP



Forward Reverse

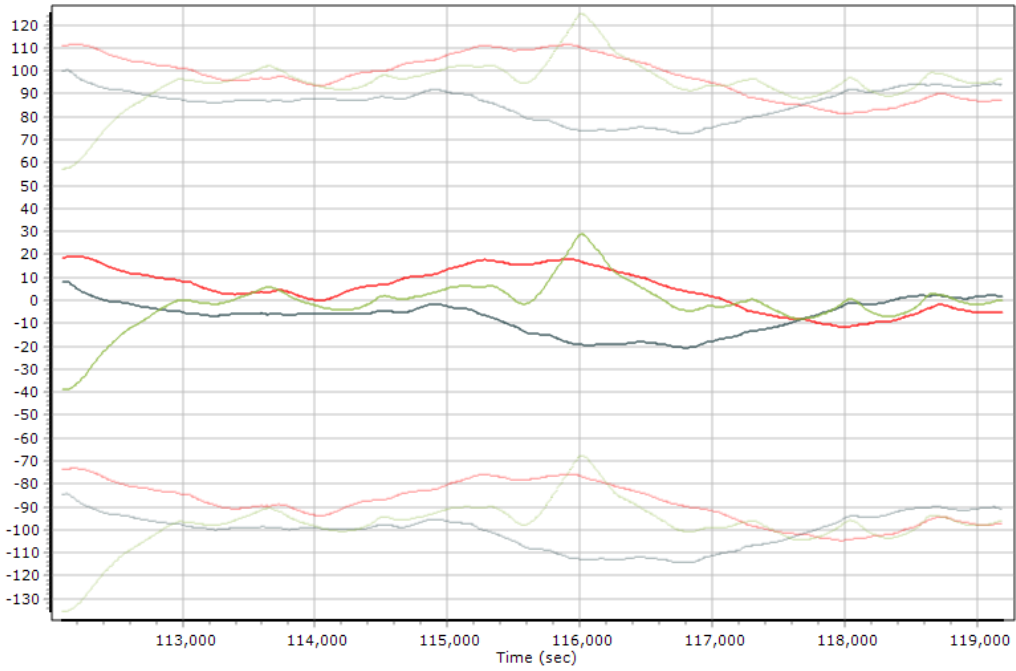
Processing mode



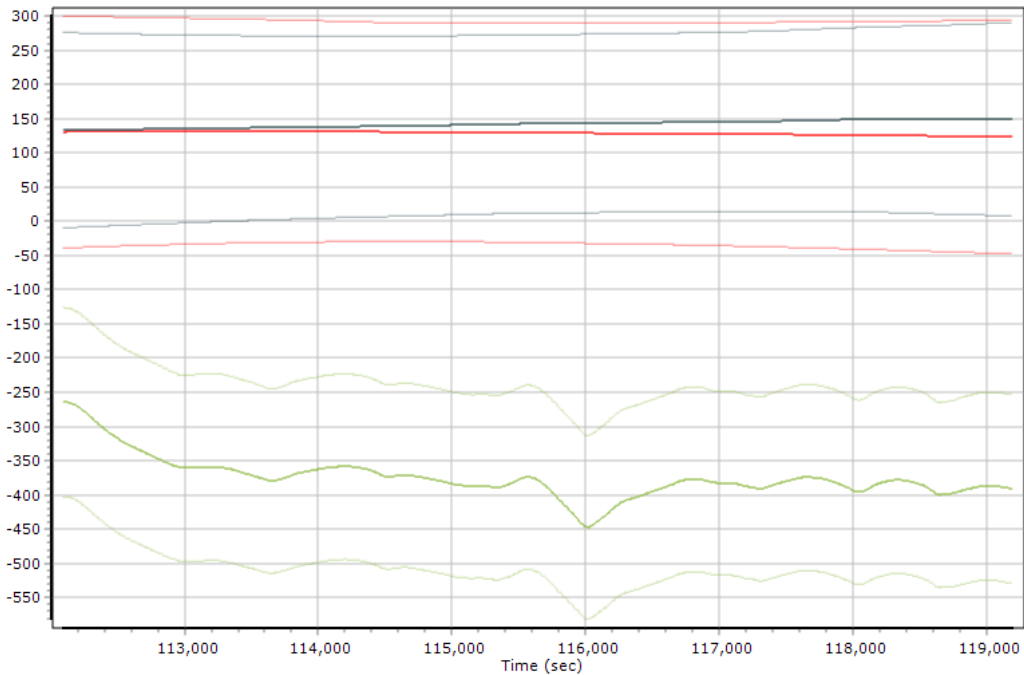
Forward Reverse

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

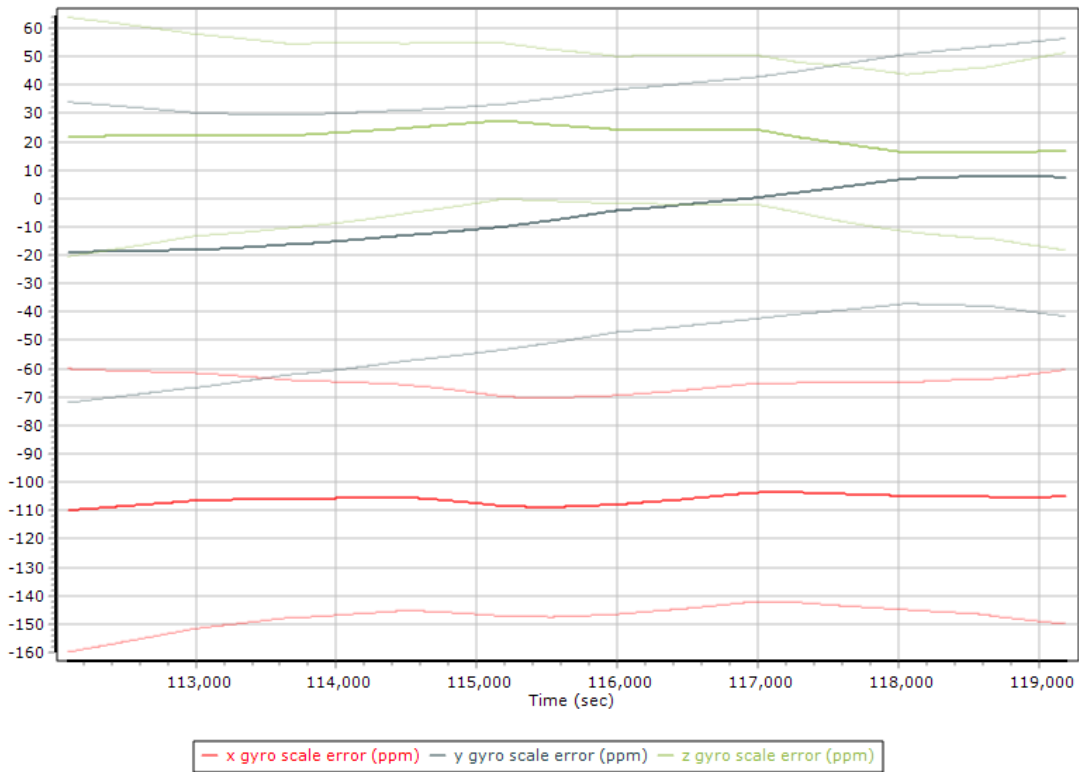
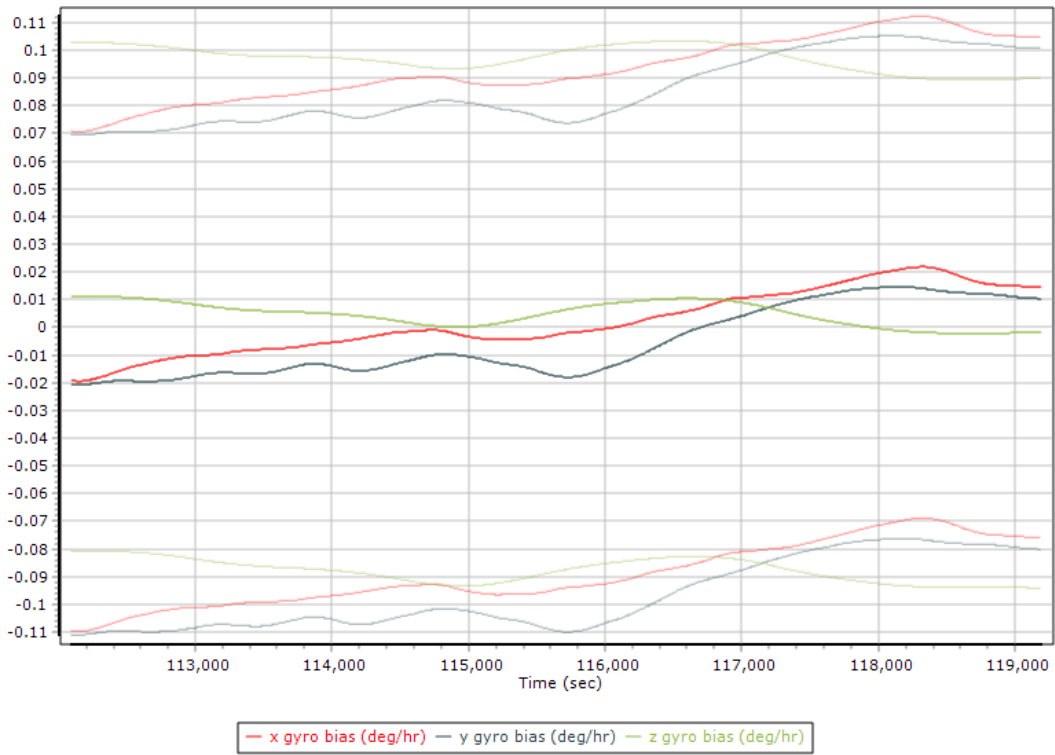
Sensor Errors



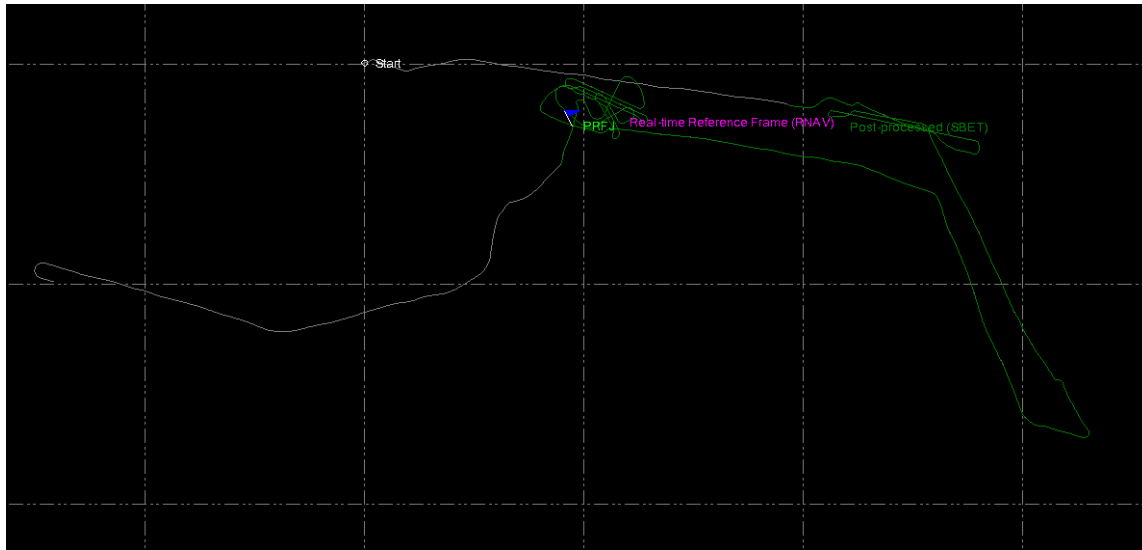
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



AZT18134B



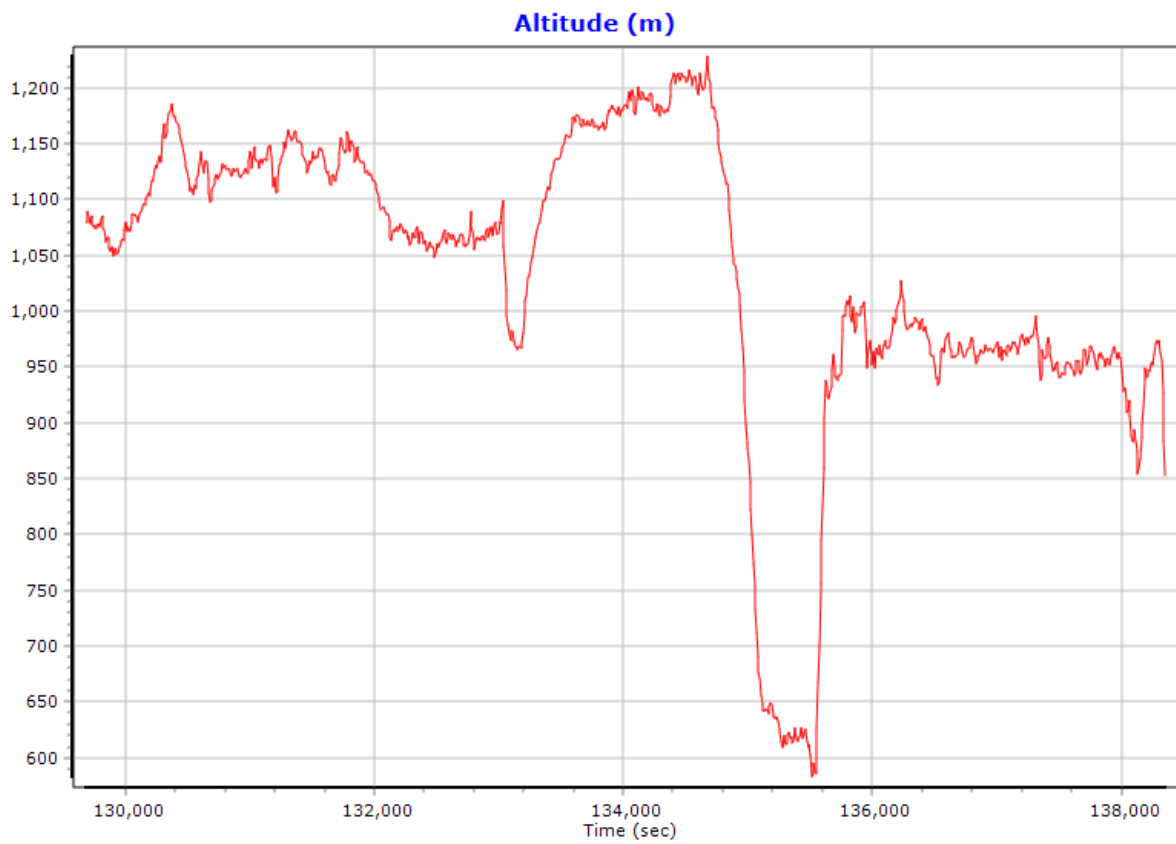
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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="3cm"/>		
	<3cm 10cm 50cm 1m 10m		

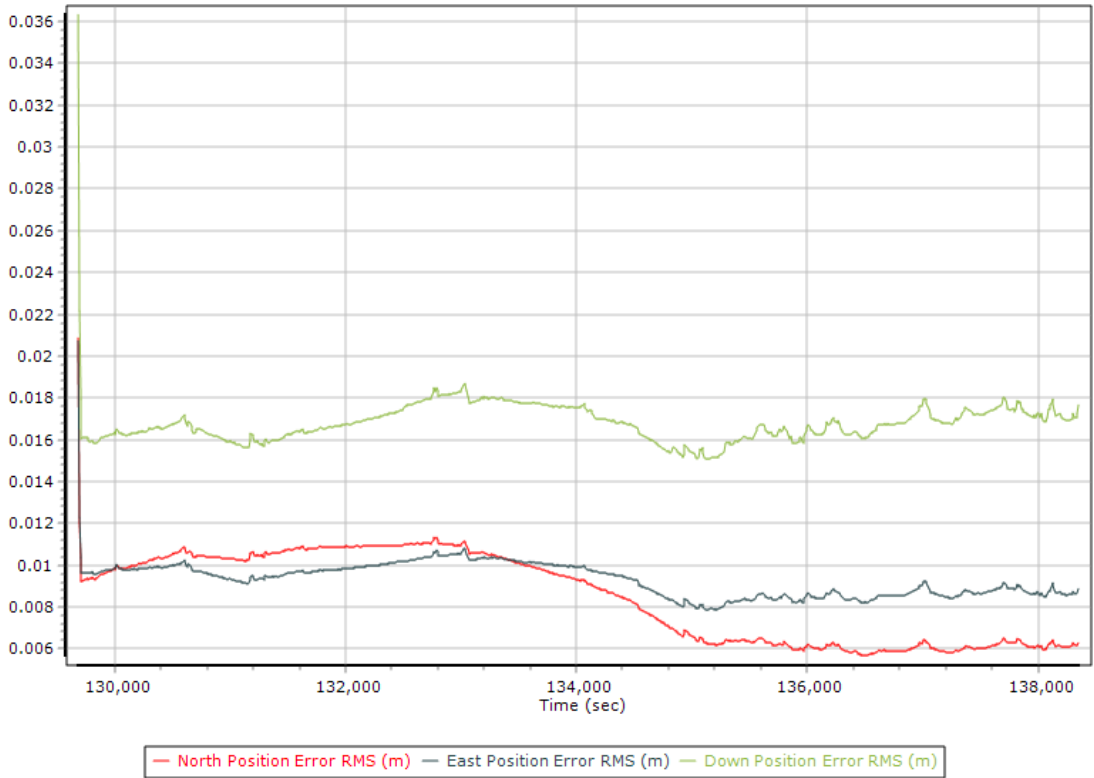
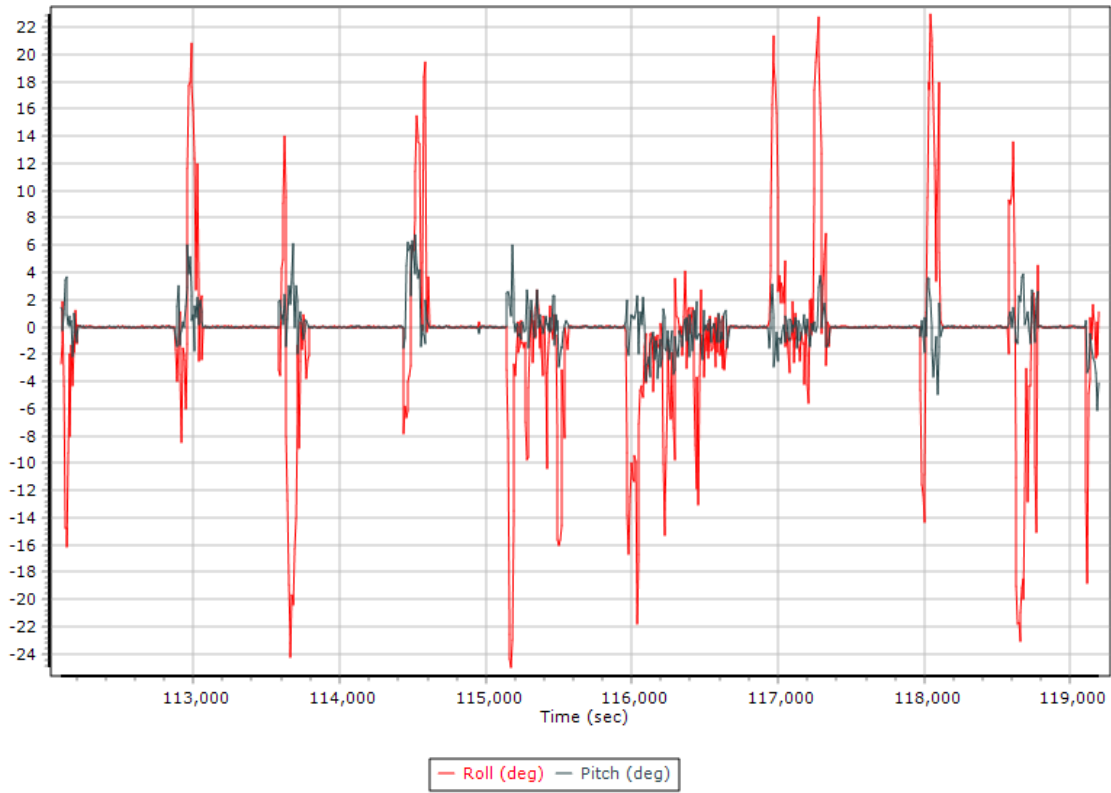
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

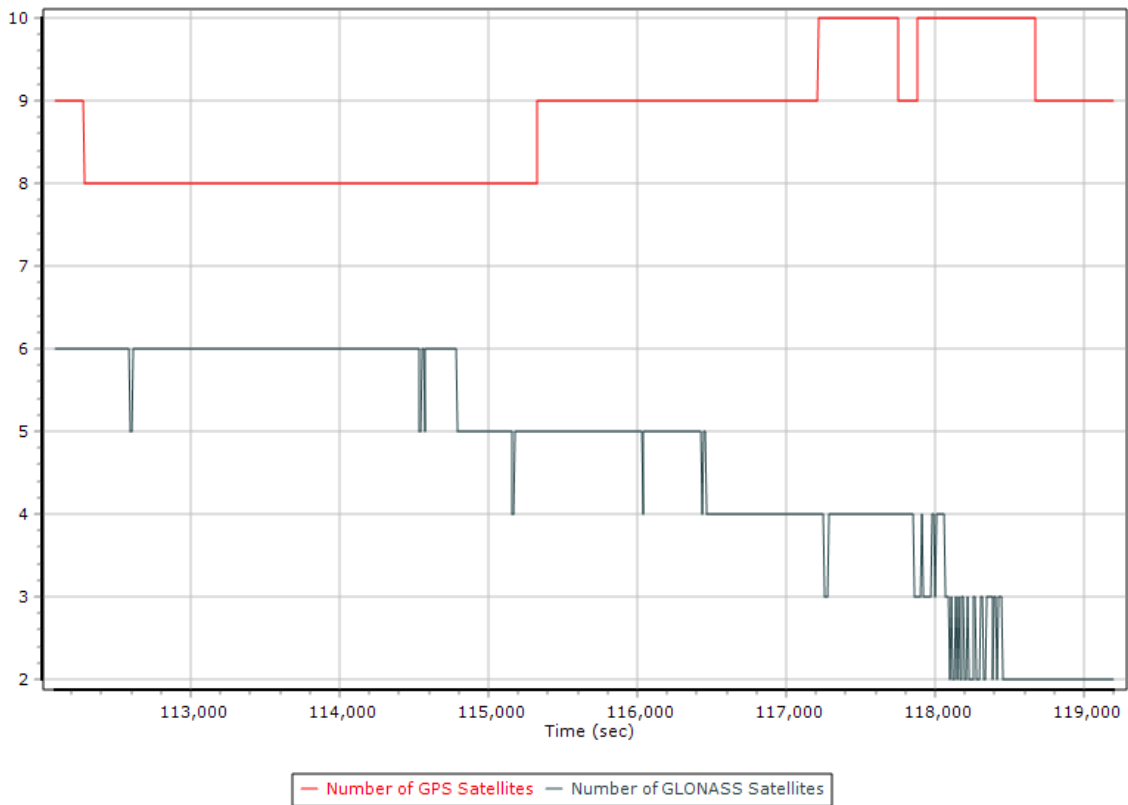
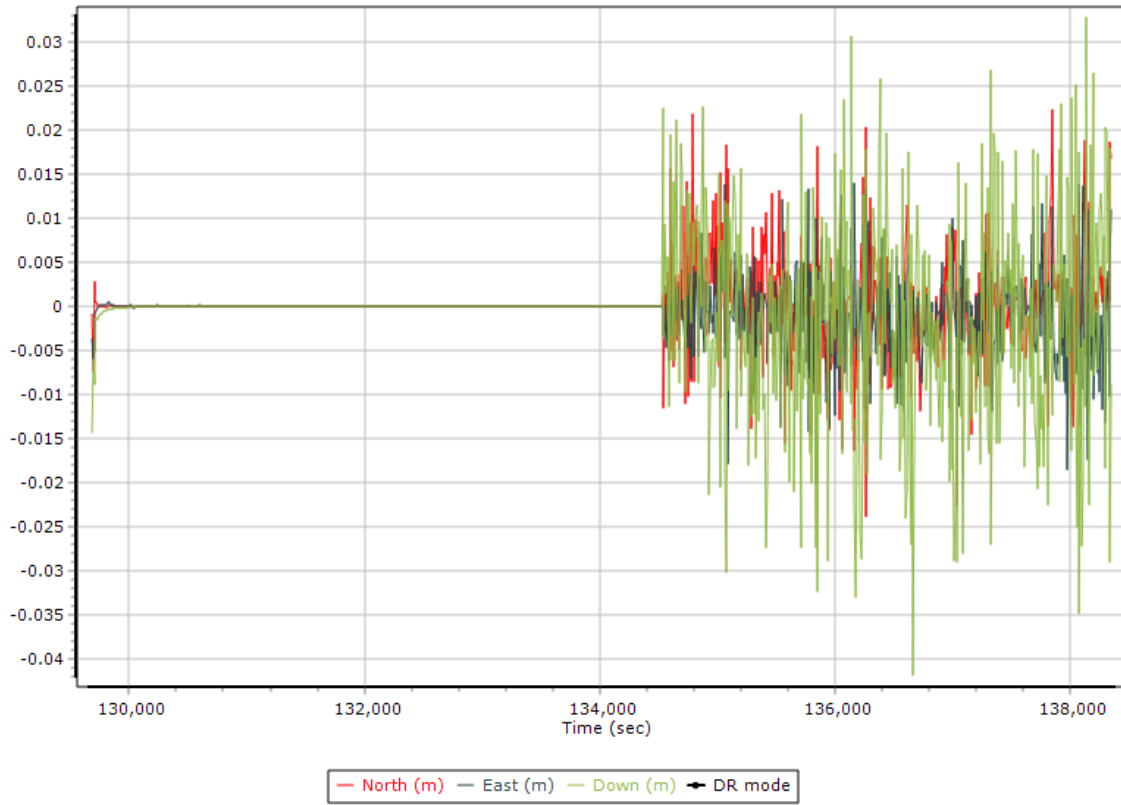
Timing

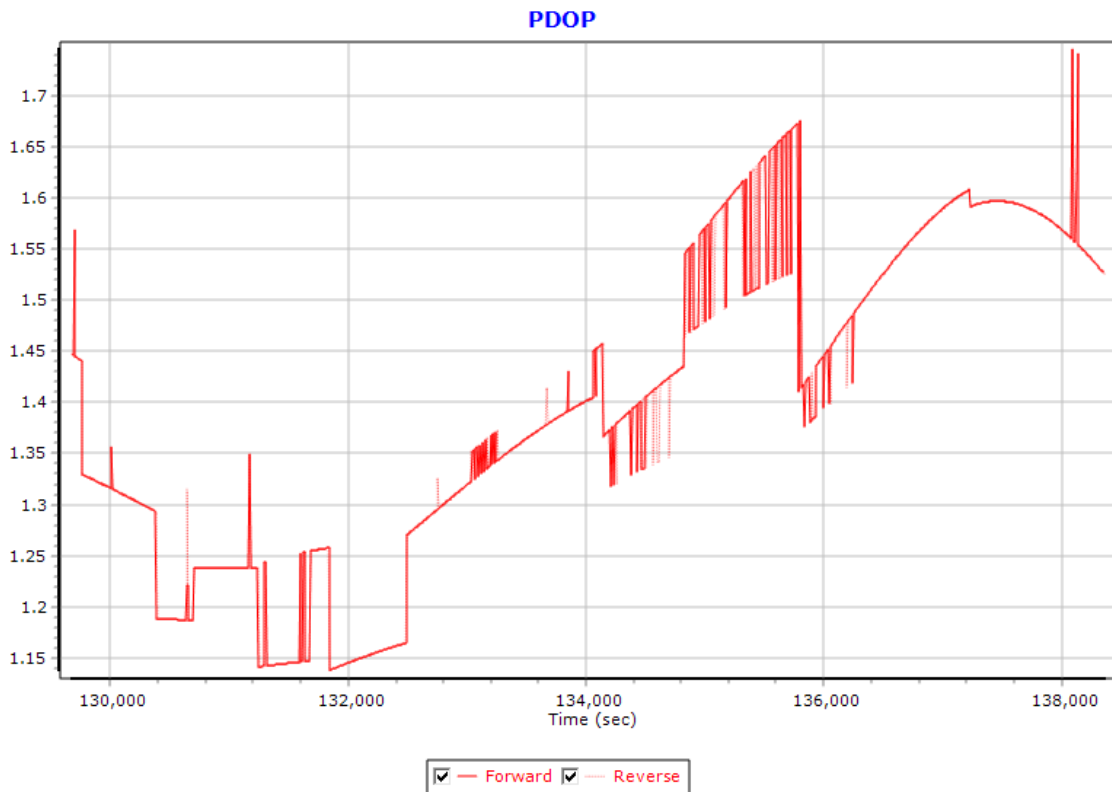
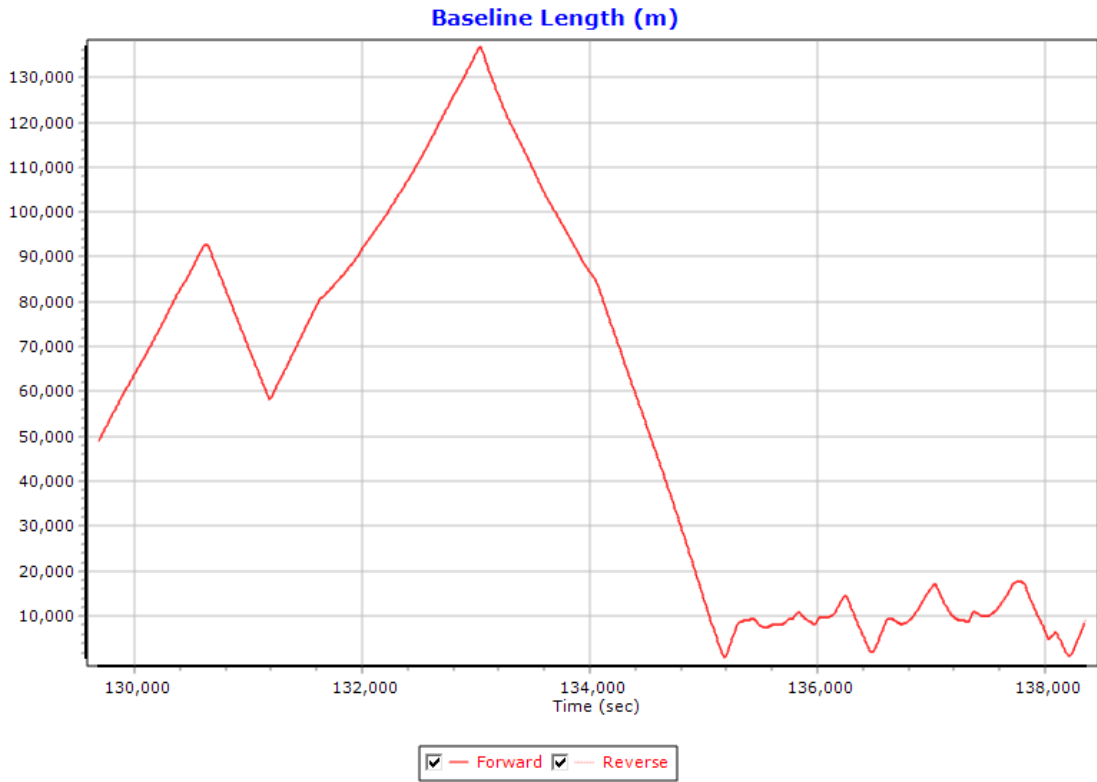
Start	129679.791	Data	Incr. (sec)
End	138359.815	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset

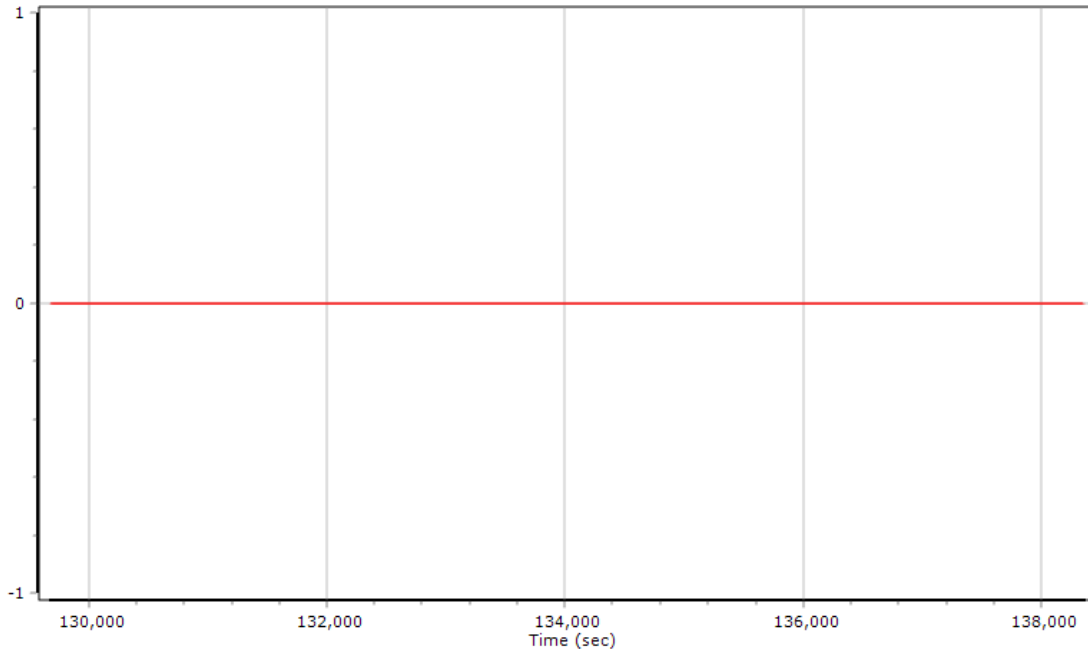








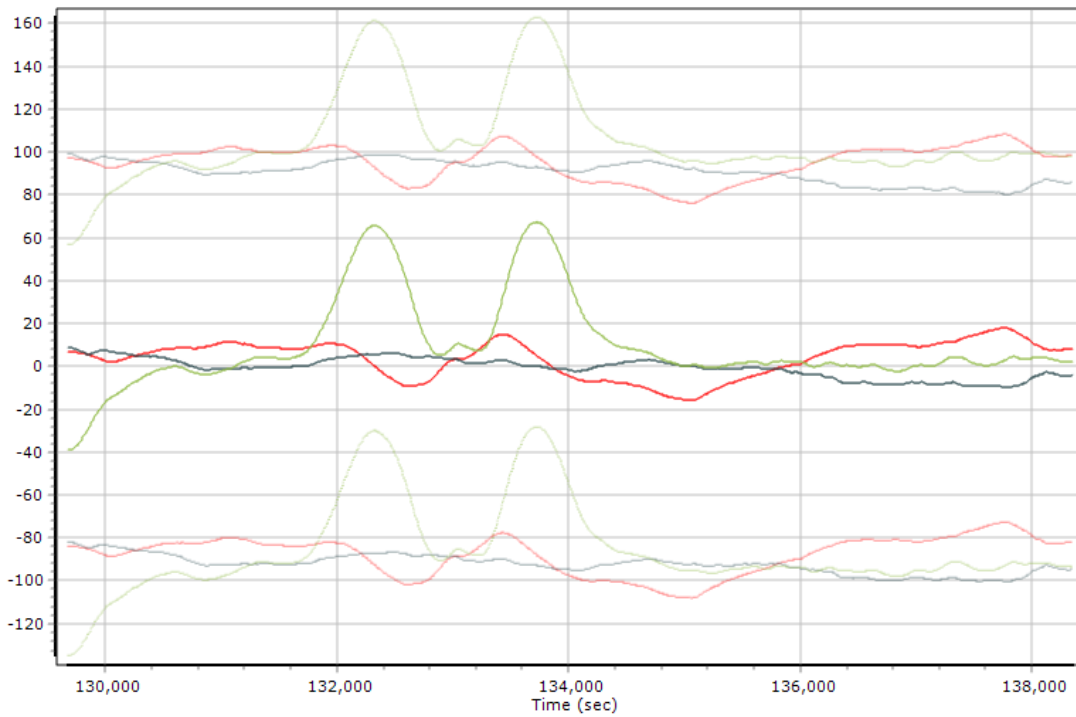
Processing mode



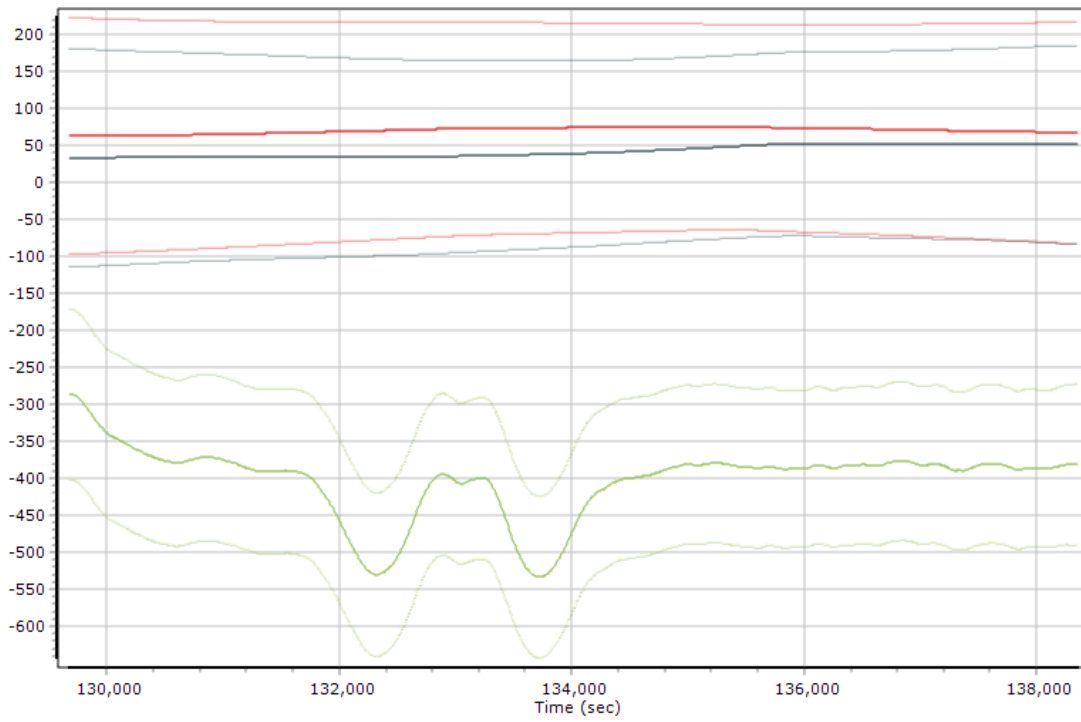
Forward Reverse

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

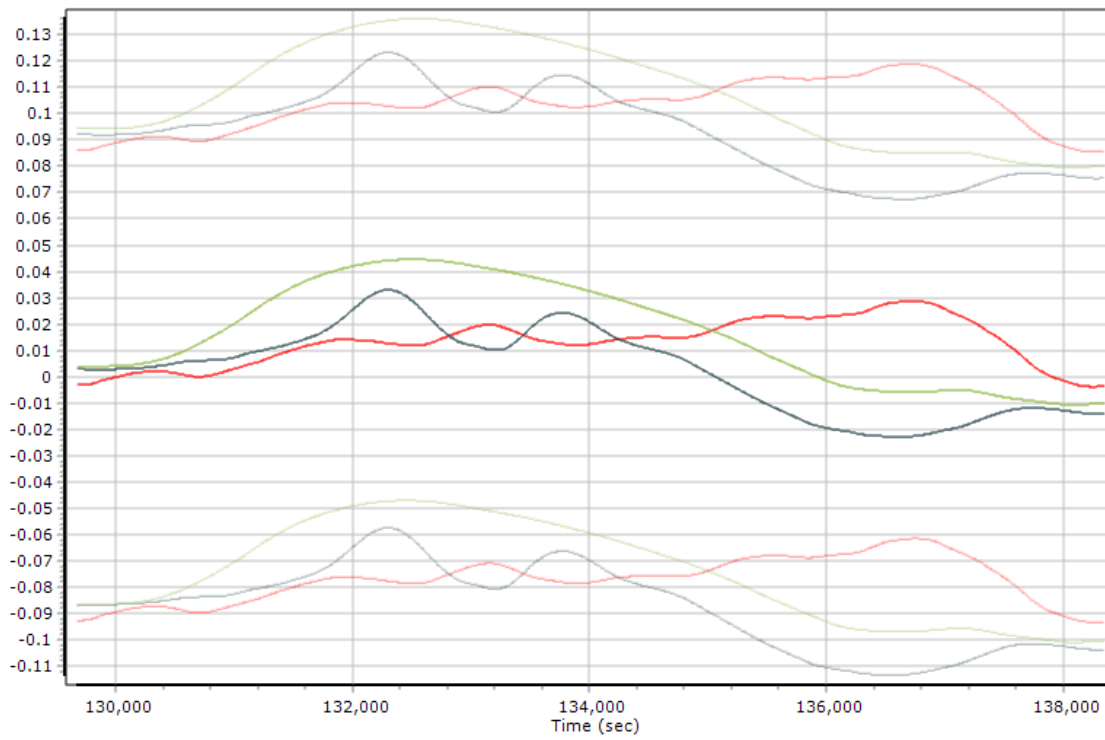
Sensor Errors



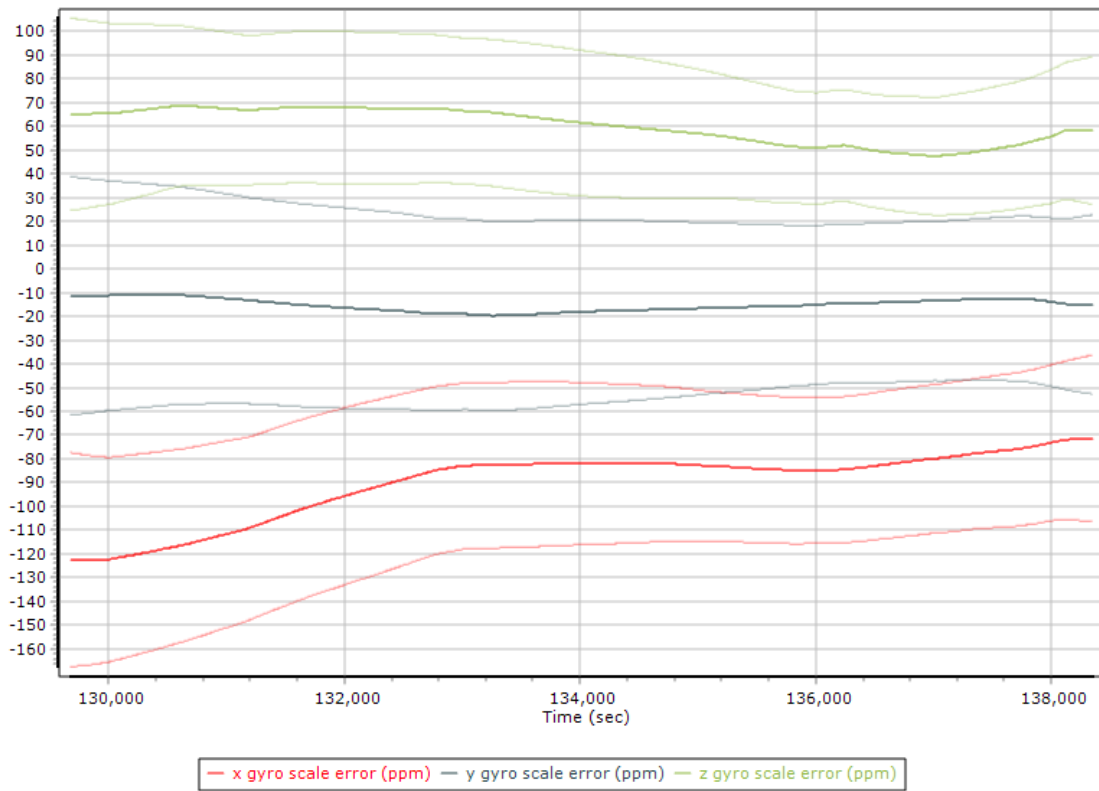
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



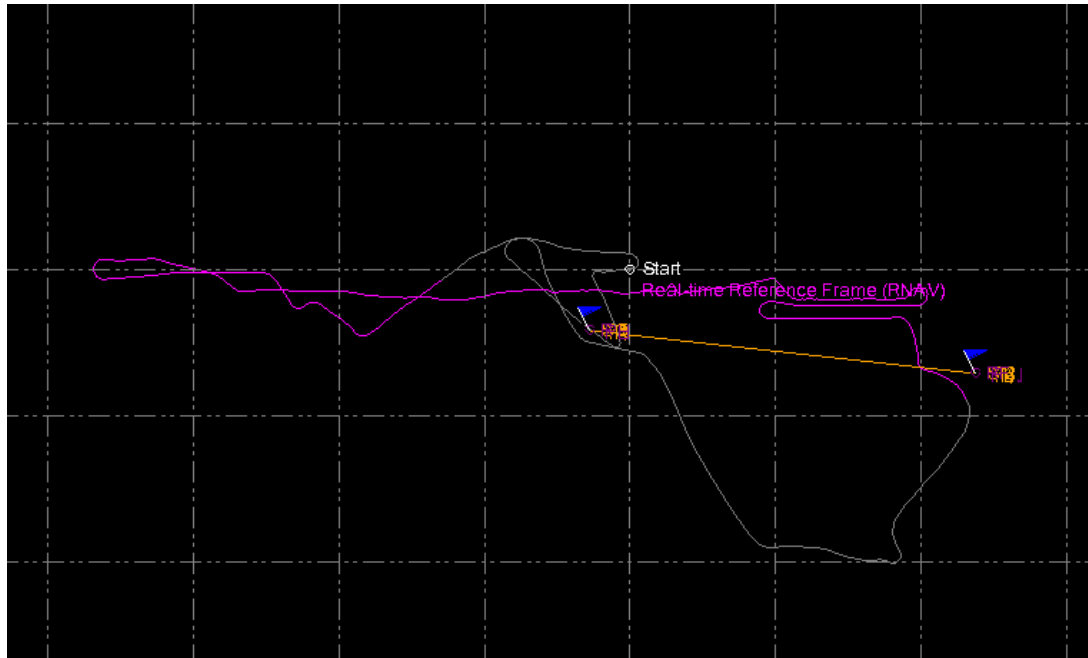
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

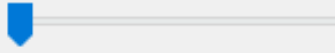


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

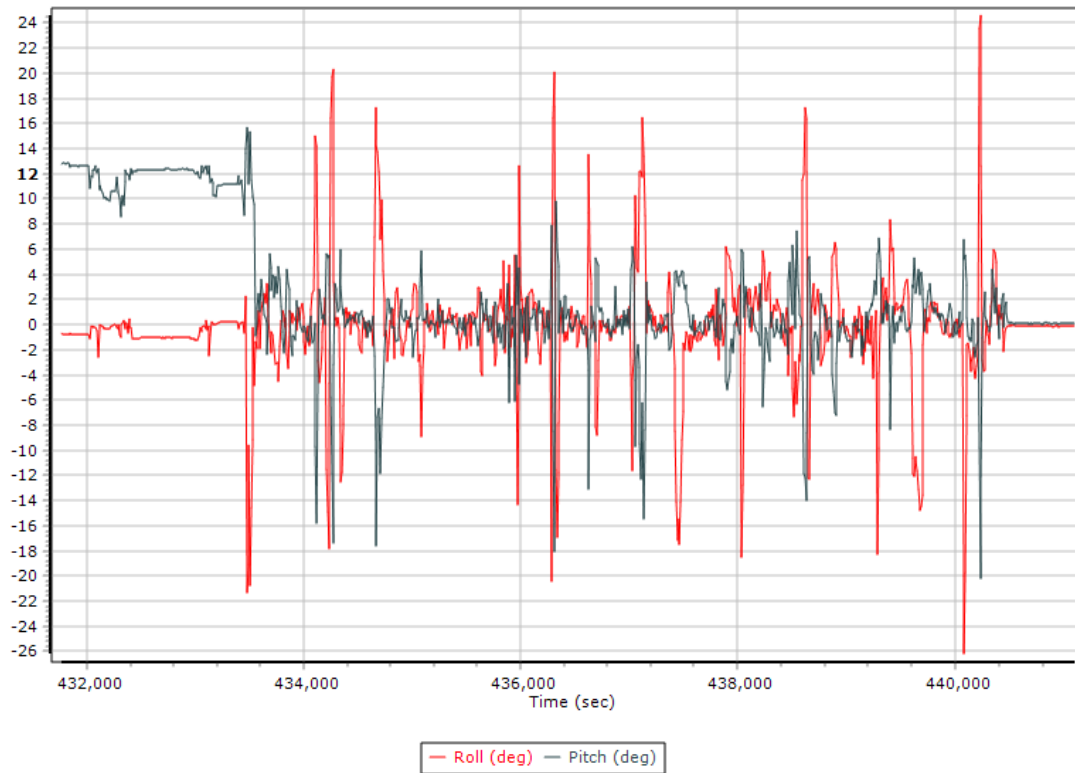
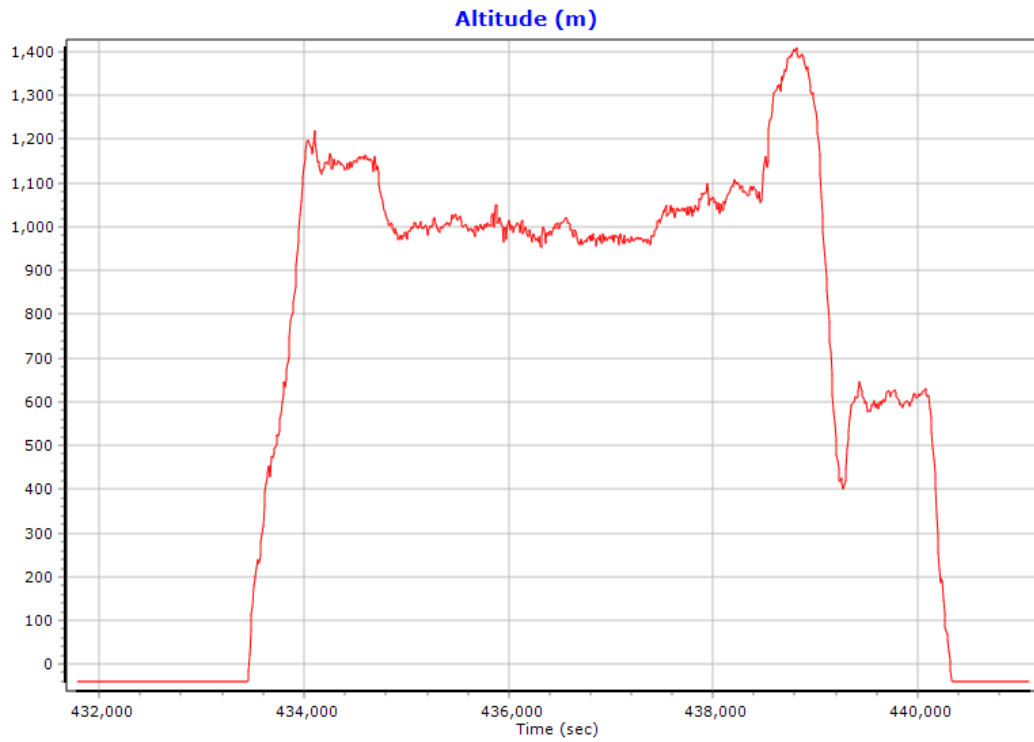


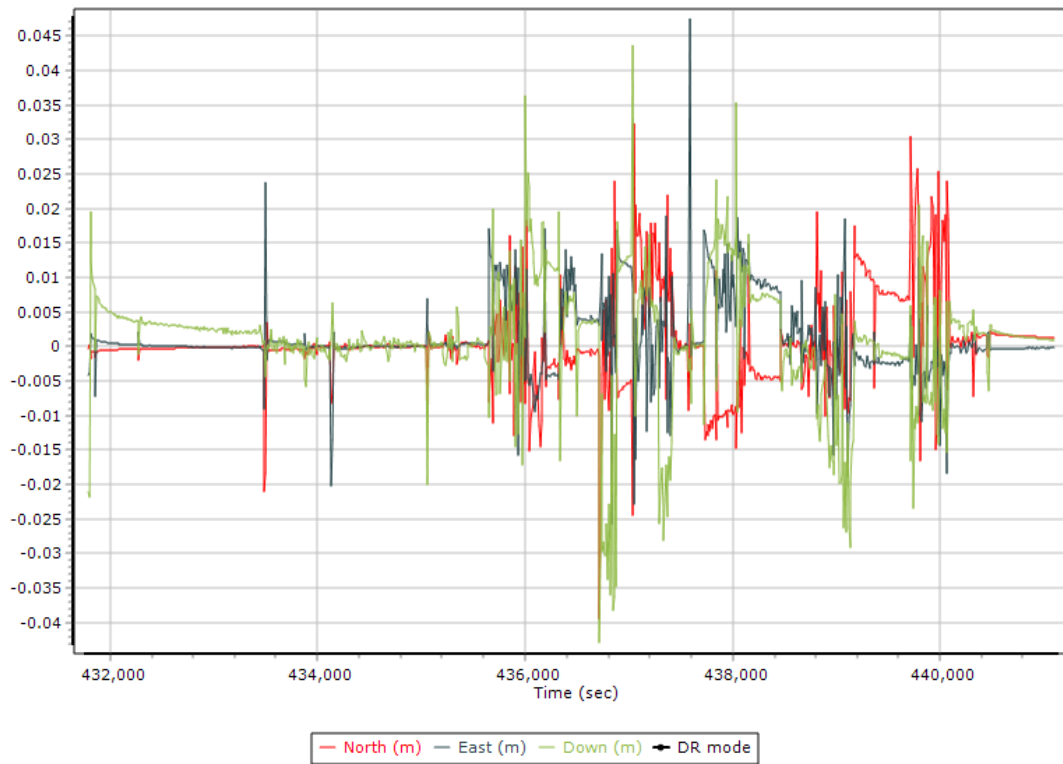
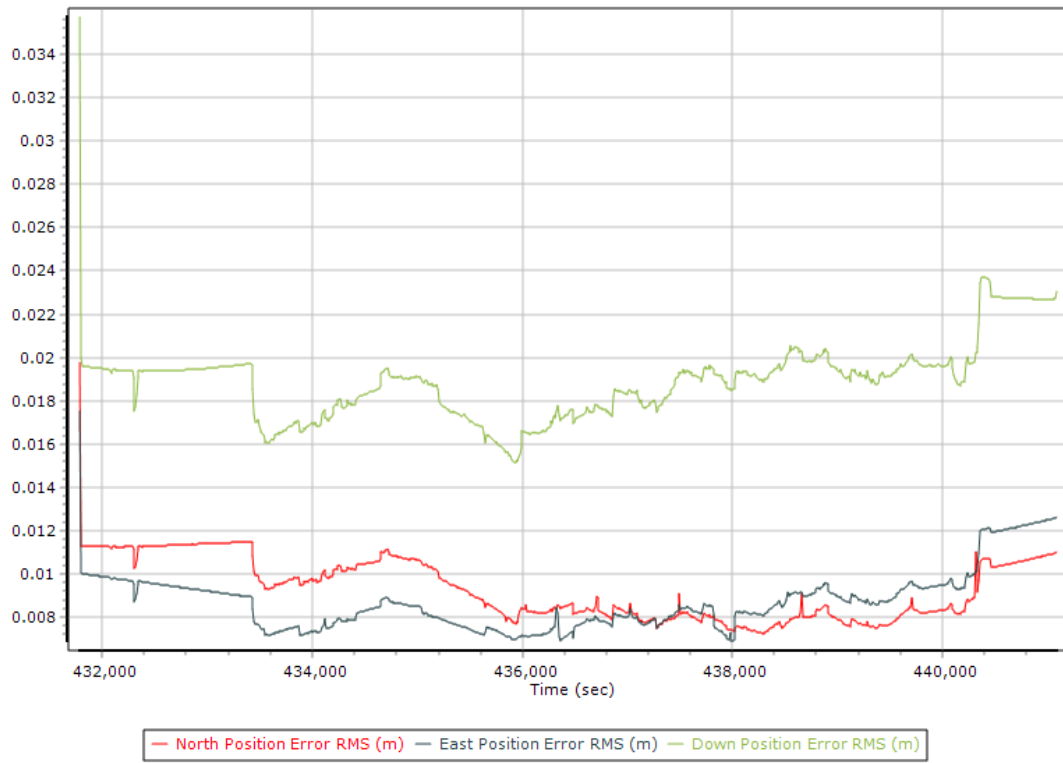
AZT18137A

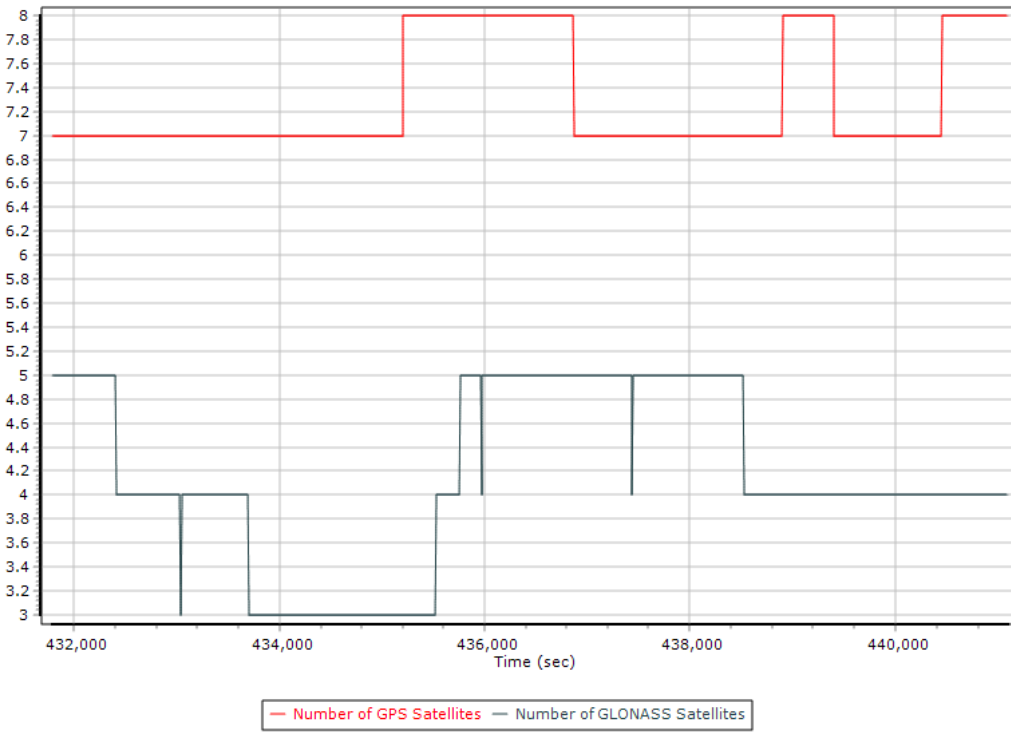


Reference to IMU Lever Arm		Reference to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 deg"/>
Reference to Primary GNSS Lever Arm		Aircraft to Reference 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="-0.738 m"/>	Z	<input type="text" value="0.000 deg"/>
Standard Deviation			
	<3cm 10cm 50cm 1m 10m		

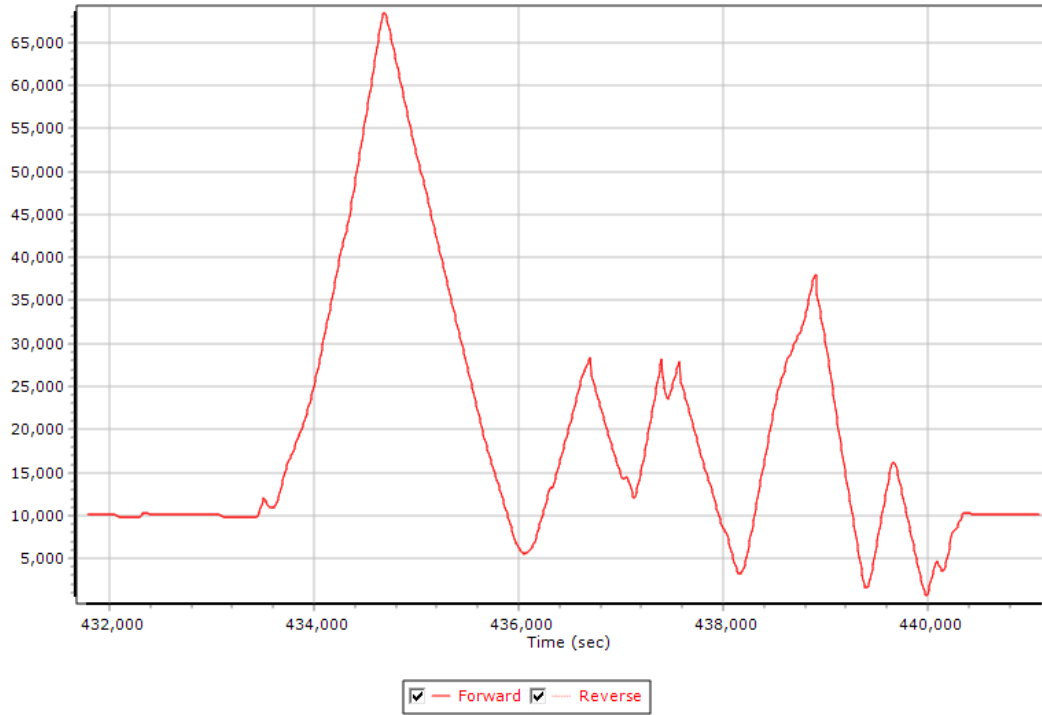
Timing			
Start	<input type="text" value="433901.731"/>	Data	Incr. (sec)
End	<input type="text" value="438242.739"/>	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000
UTC Offset	<input type="text" value="18.000"/>		



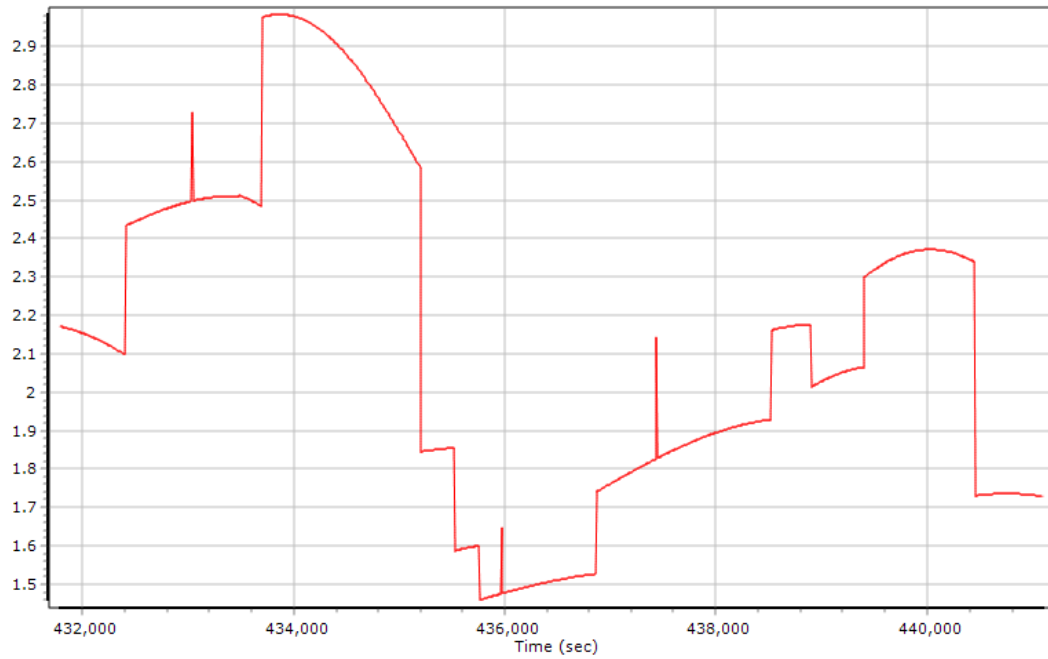




Baseline Length (m)

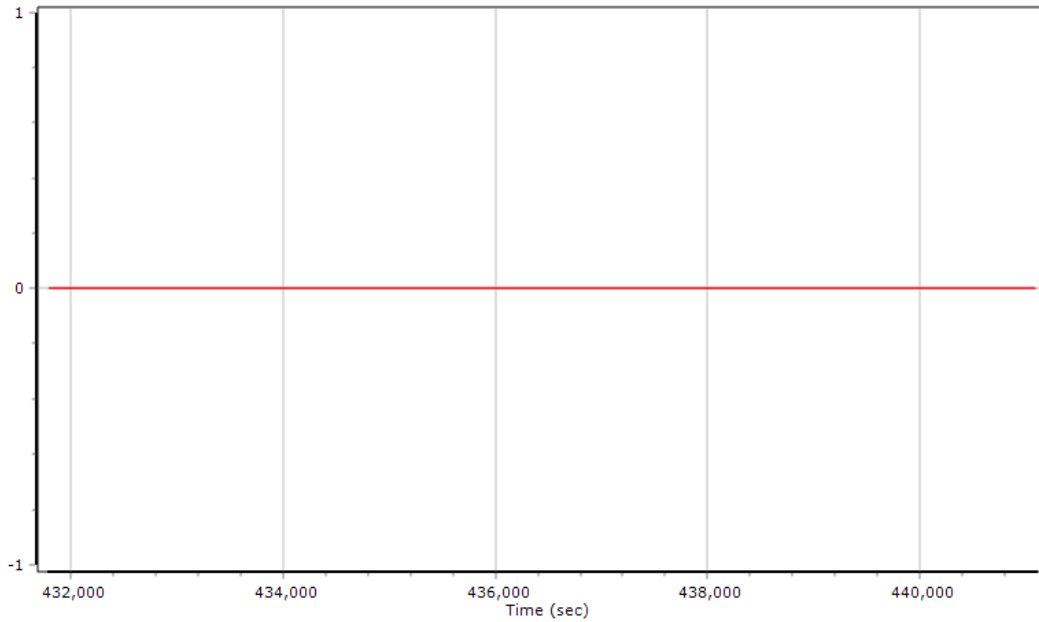


PDOP



Forward Reverse

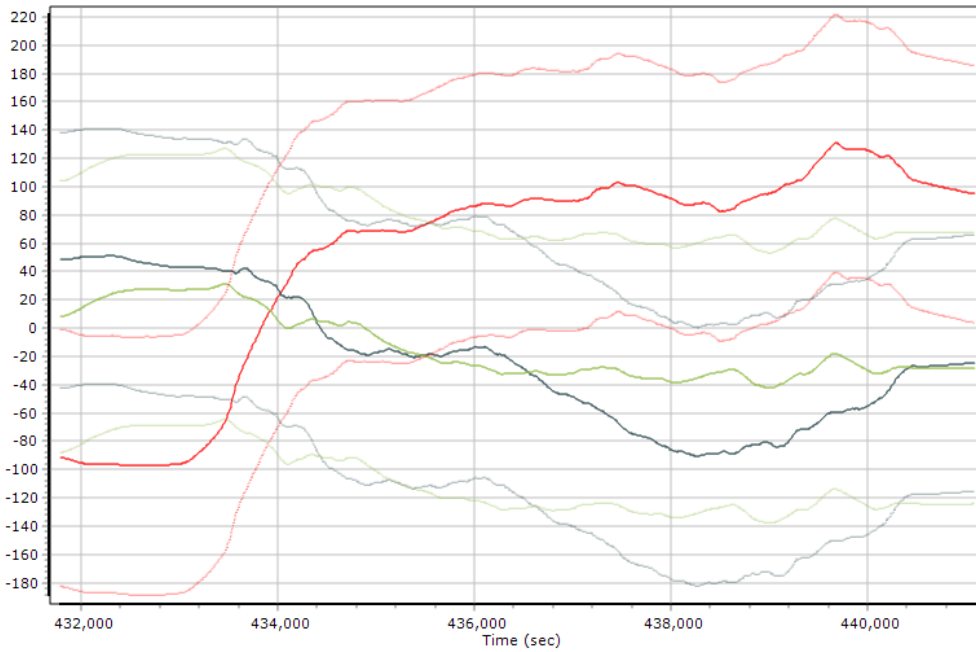
Processing mode



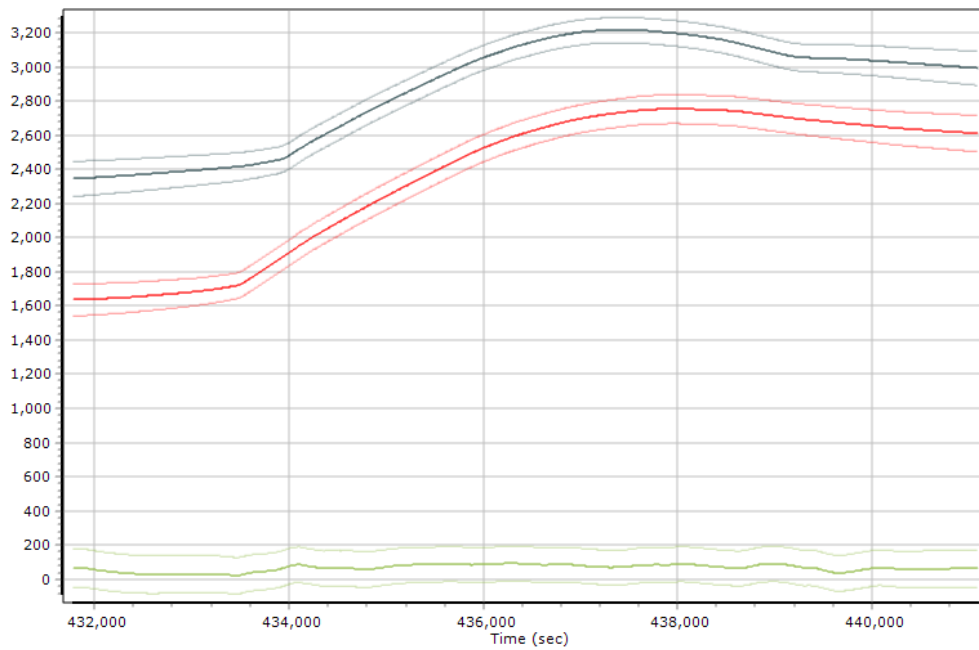
Forward Reverse

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

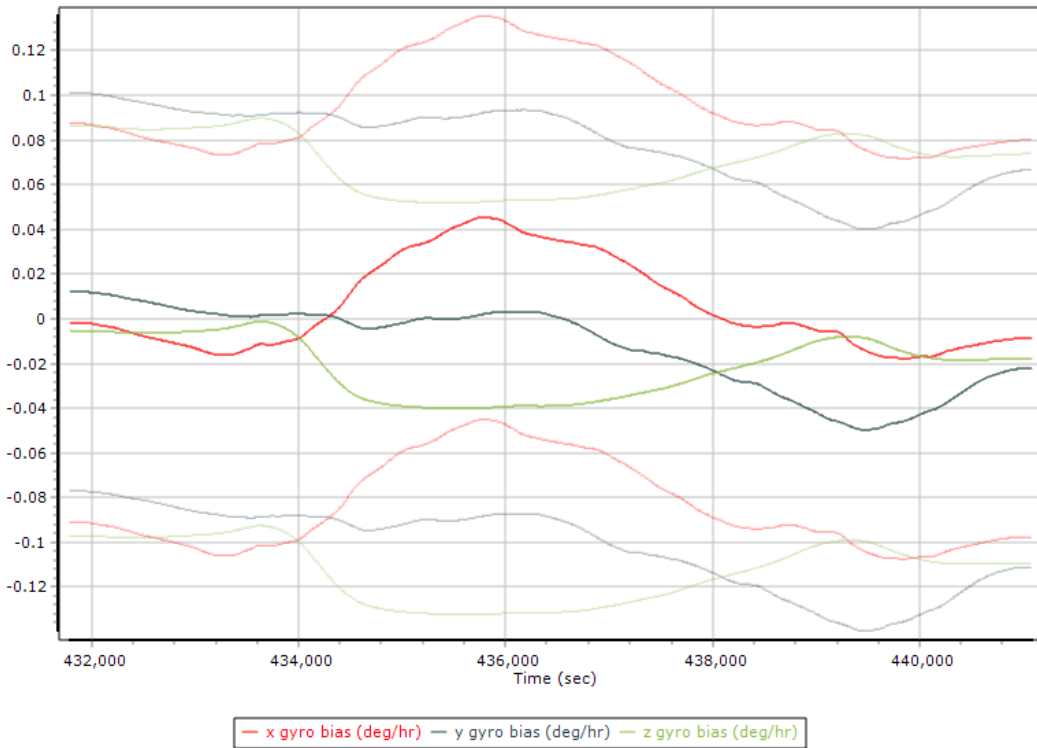
Sensor Errors



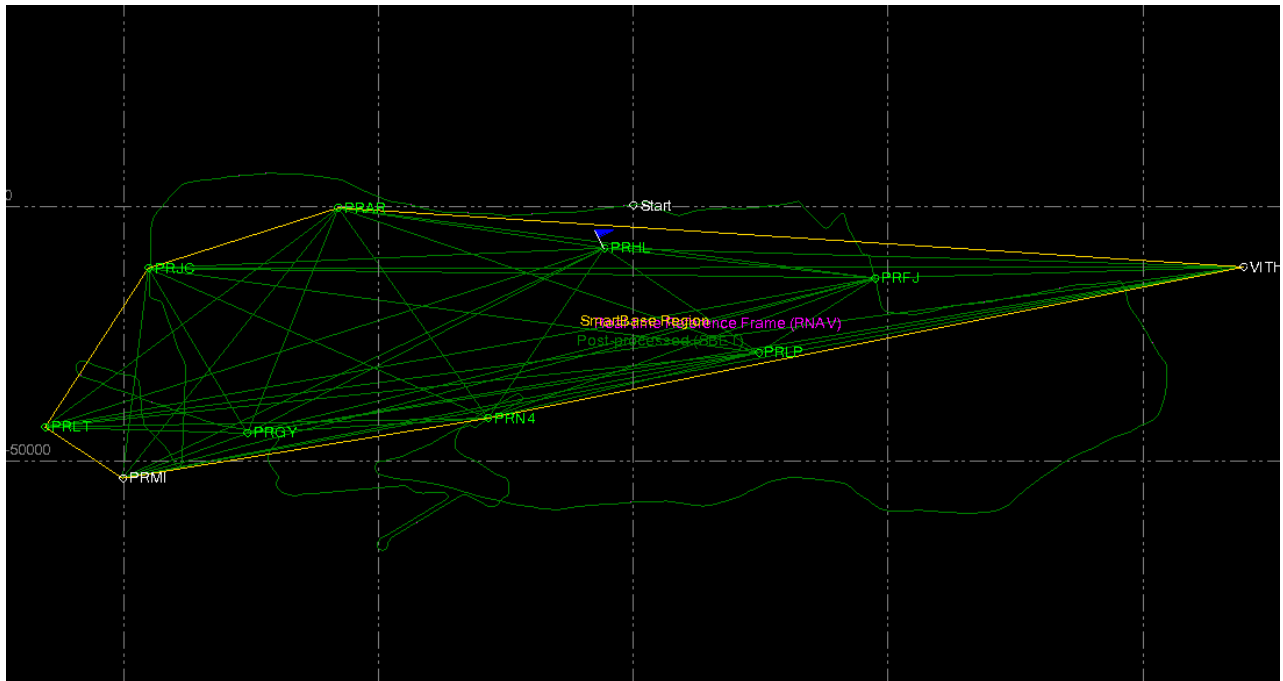
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)

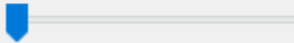


— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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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.

Timing

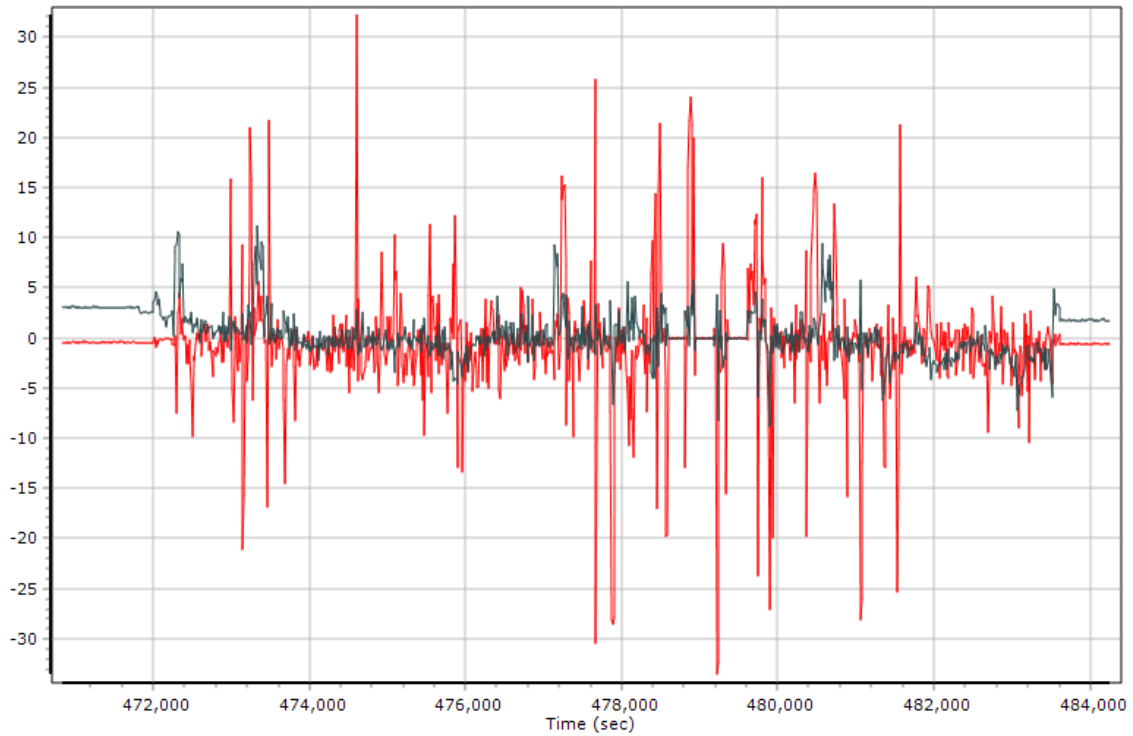
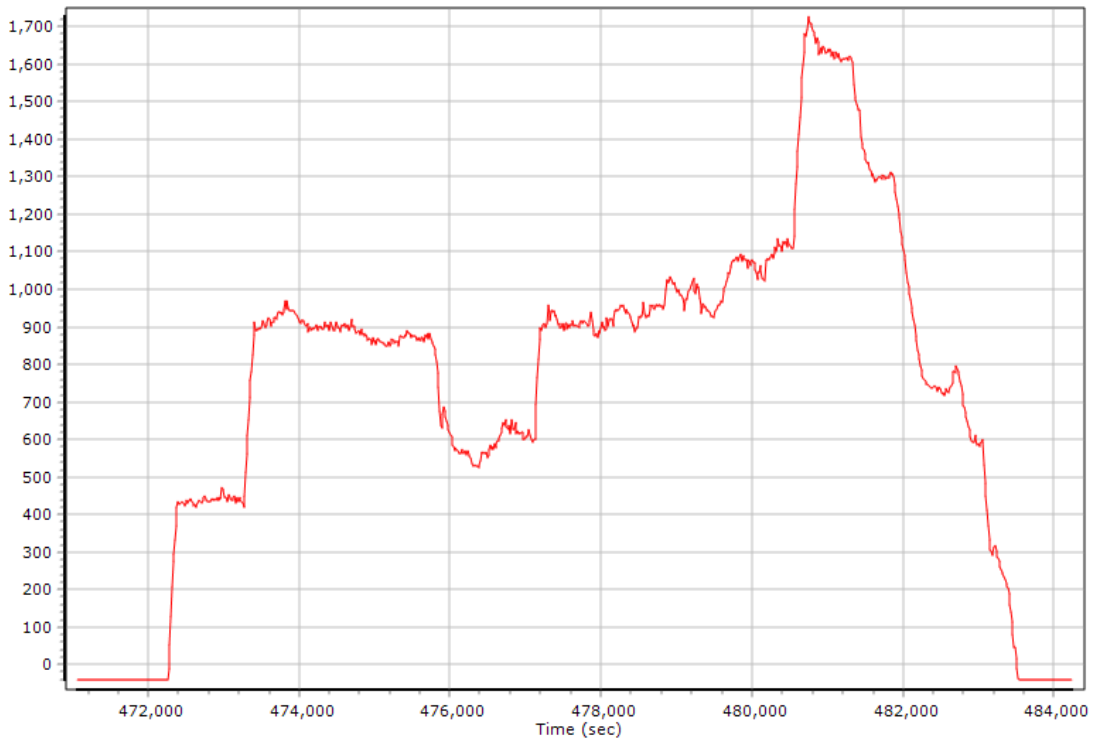
Start: 470830.000
End: 484261.000

Entire time interval
 Seconds of start week

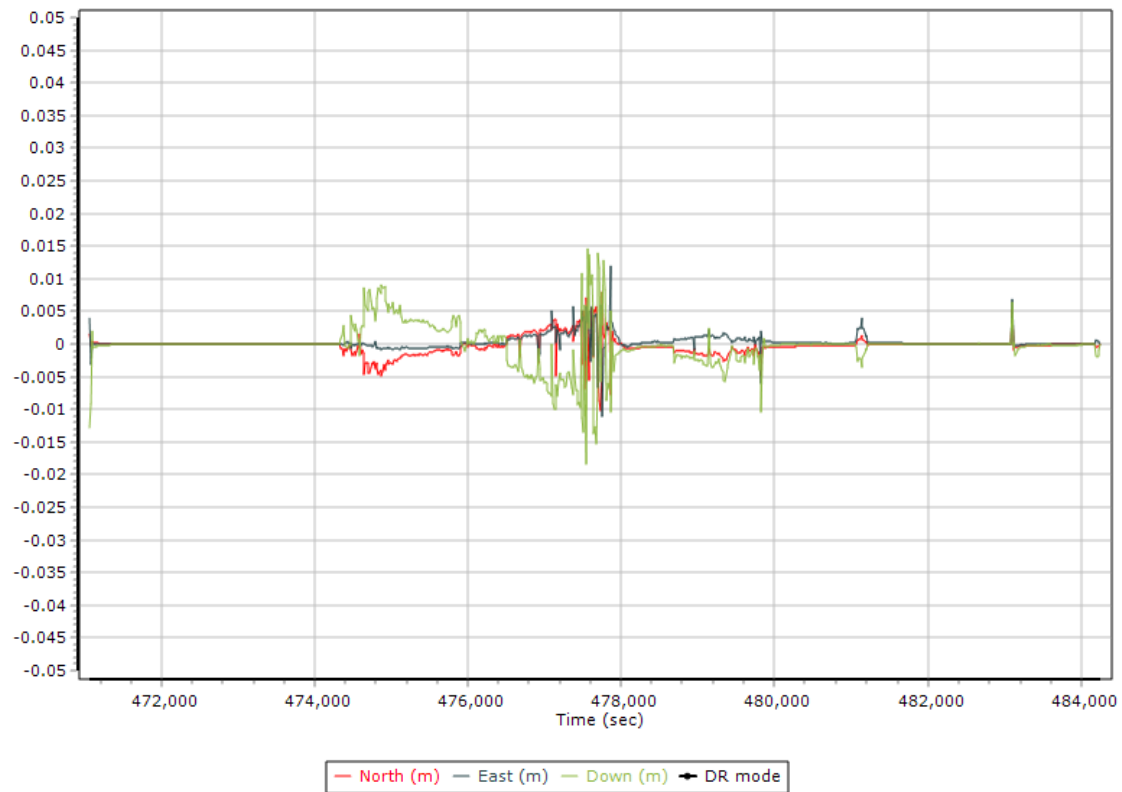
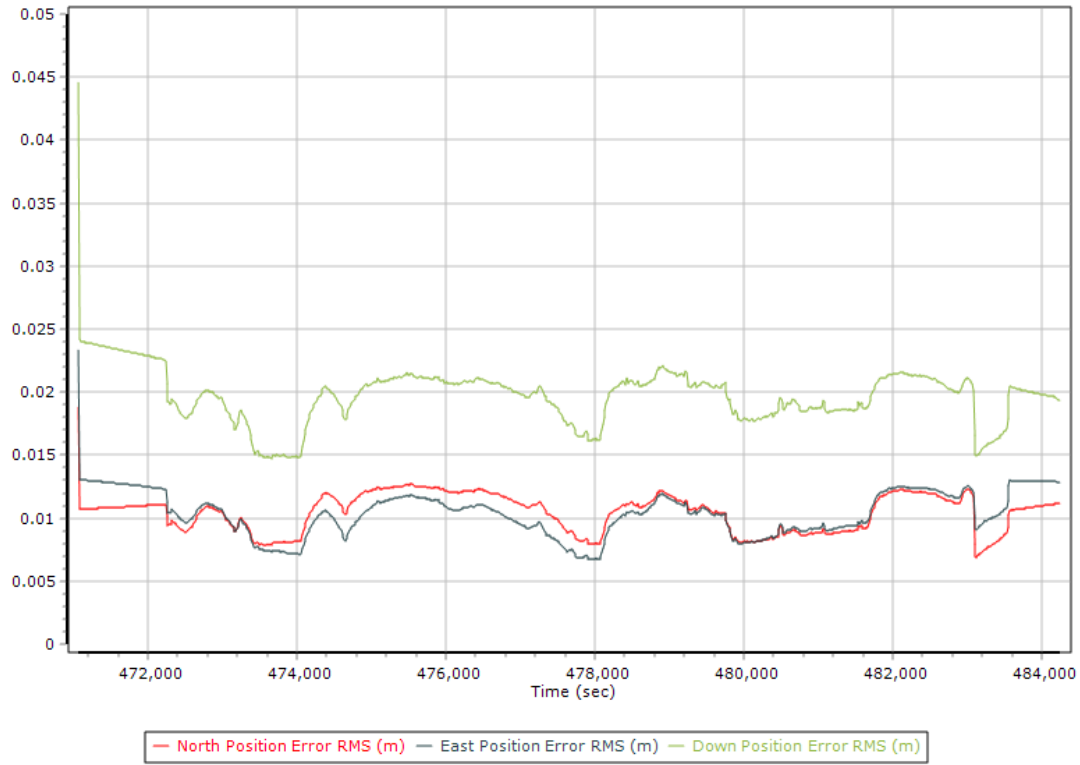
UTC Offset: 18.000

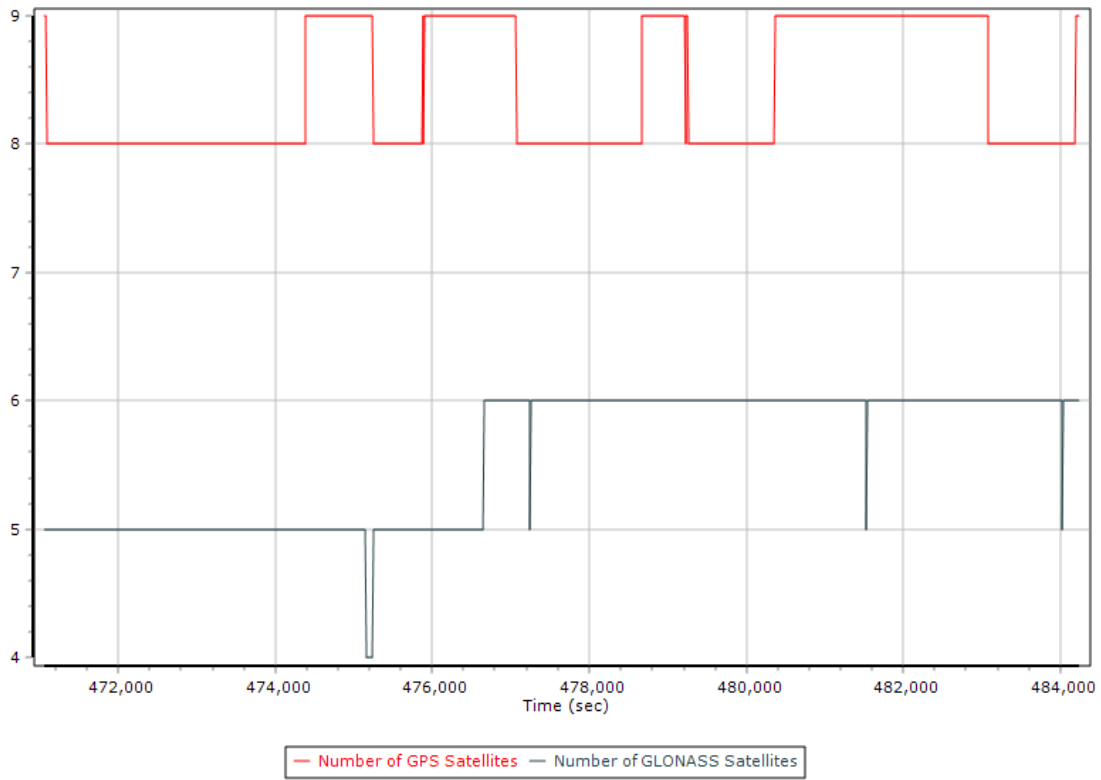
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

Altitude (m)

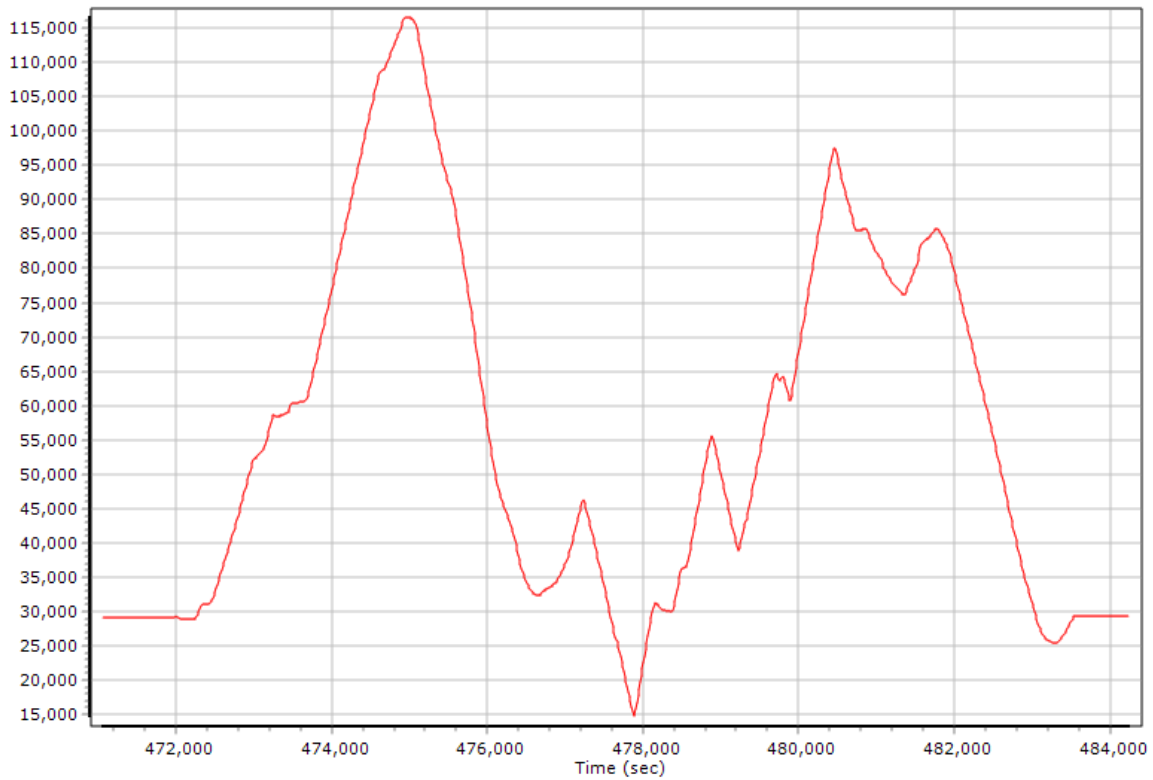


— Roll (deg) — Pitch (deg)

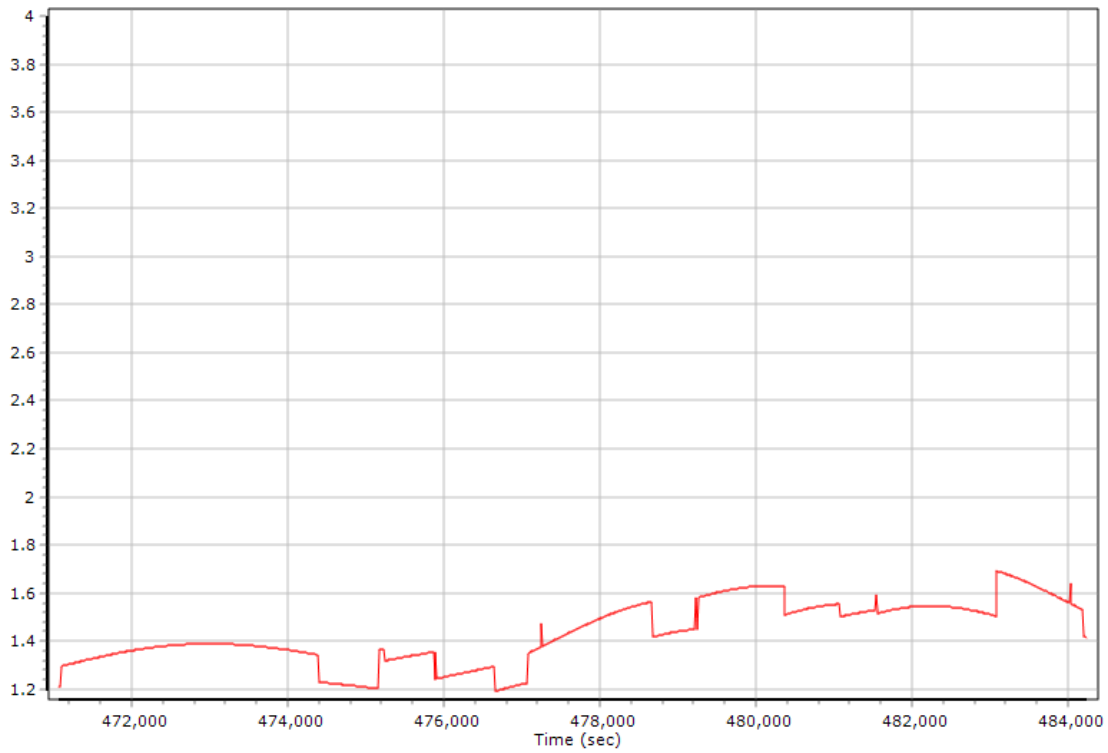




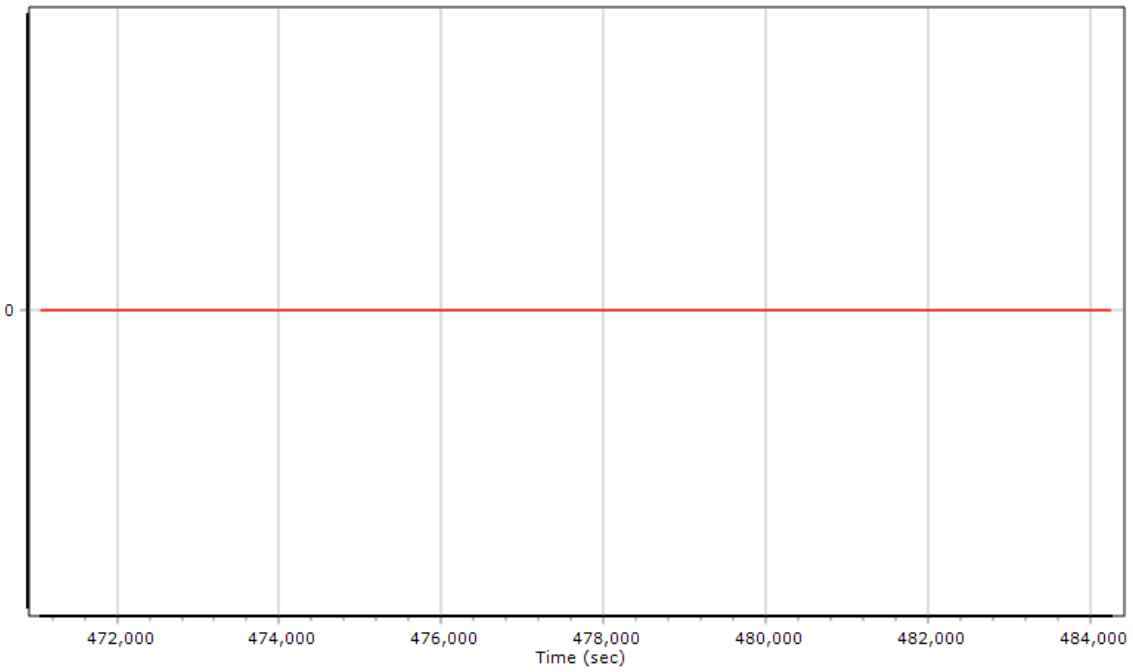
Baseline Length (m)



PDOP

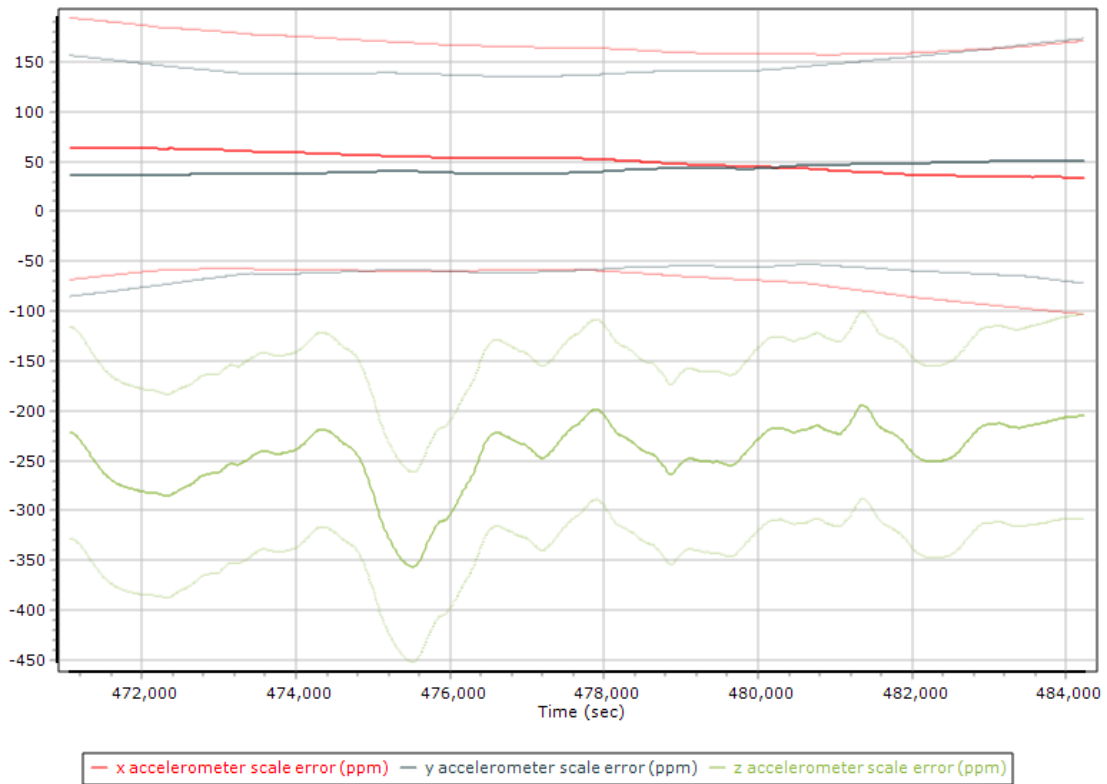
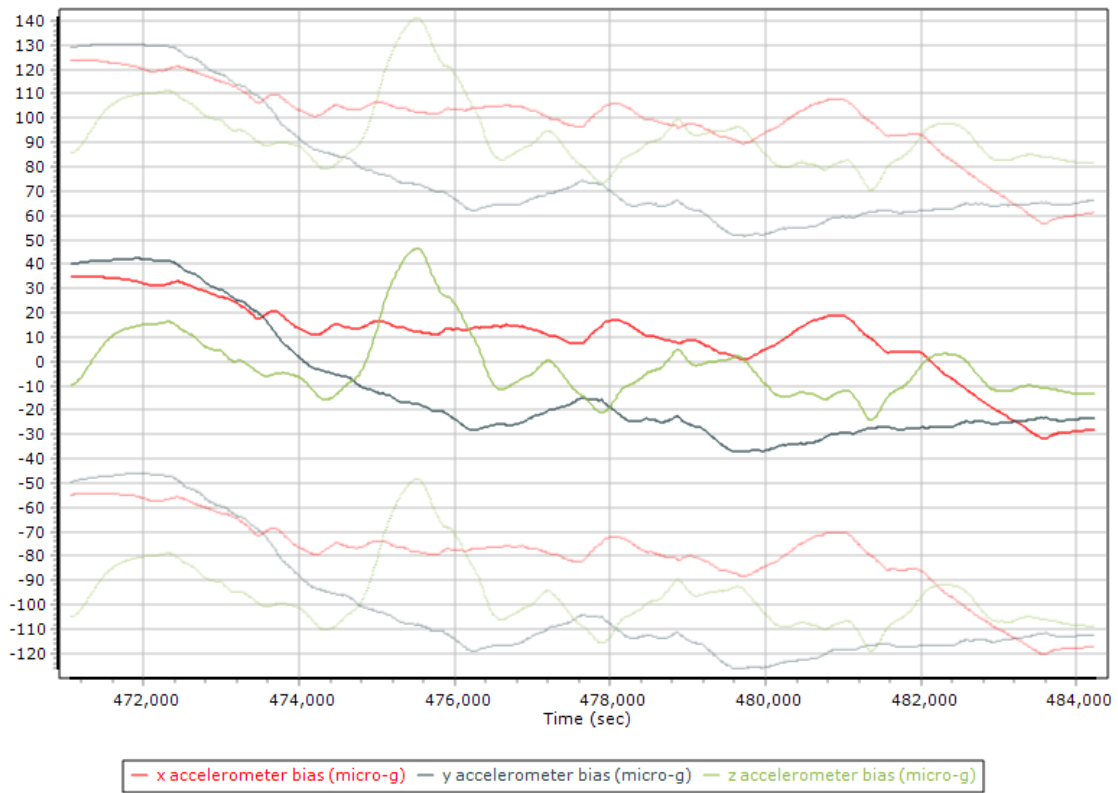


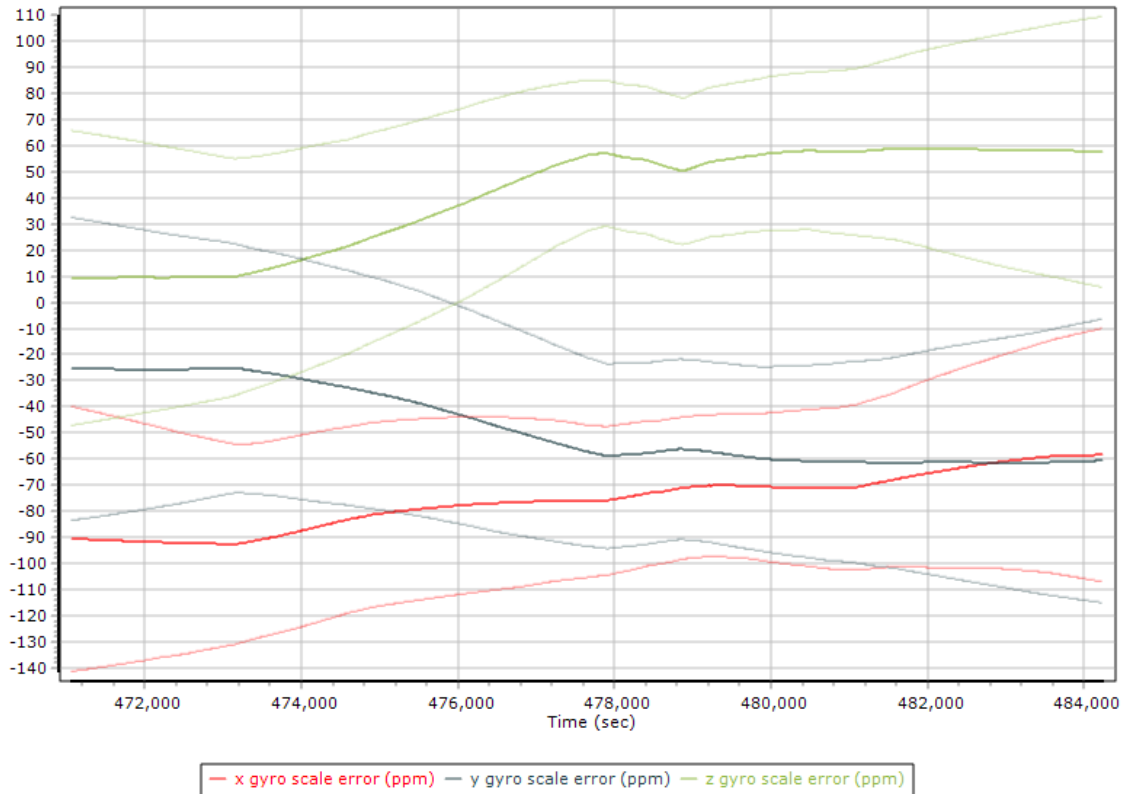
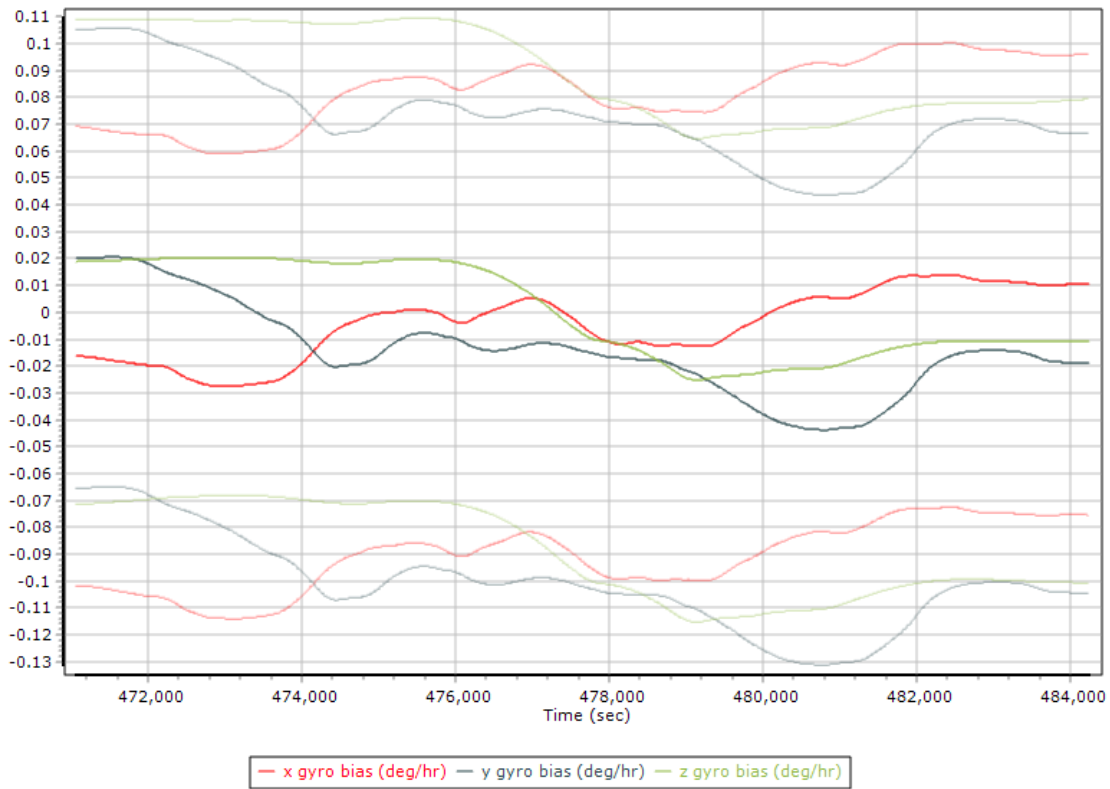
Processing Mode



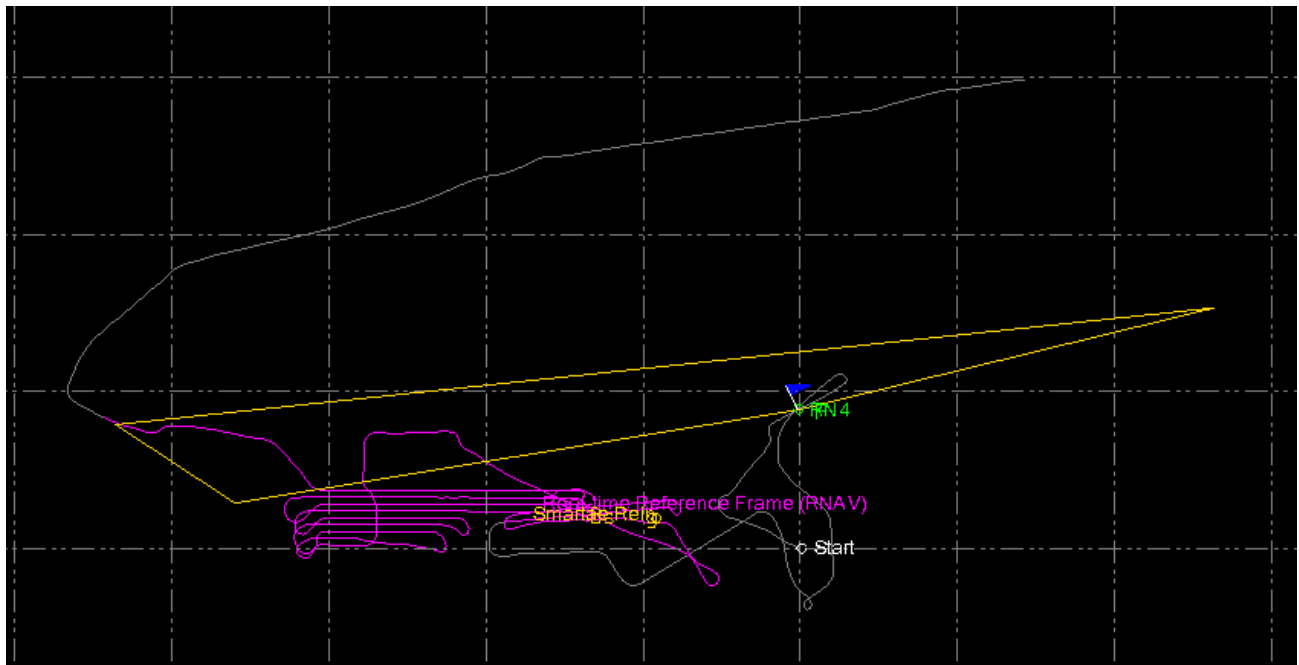
Forward Reverse

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





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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="-0.738 m"/>	Z	<input type="text" value="0.000 deg"/>
Standard Deviation	<input type="range" value="3cm 10cm 50cm 1m 10m"/>		

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

Timing

Start

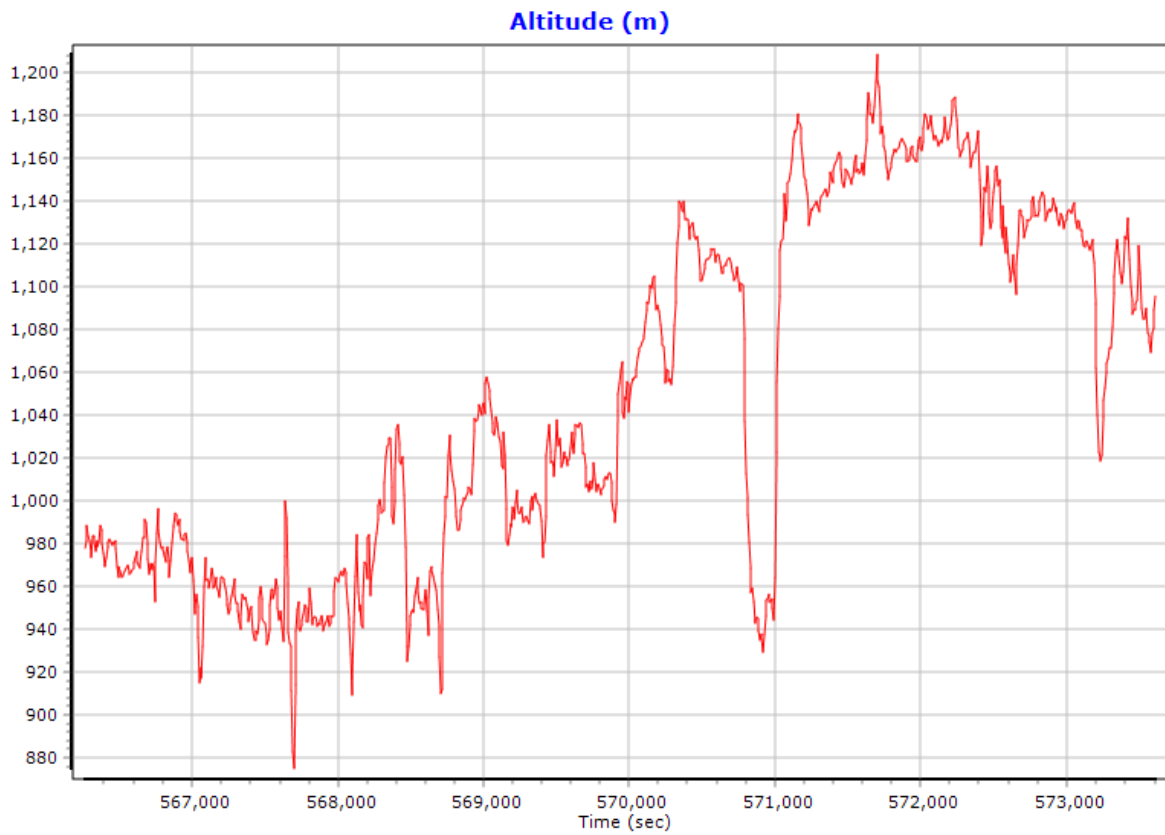
End

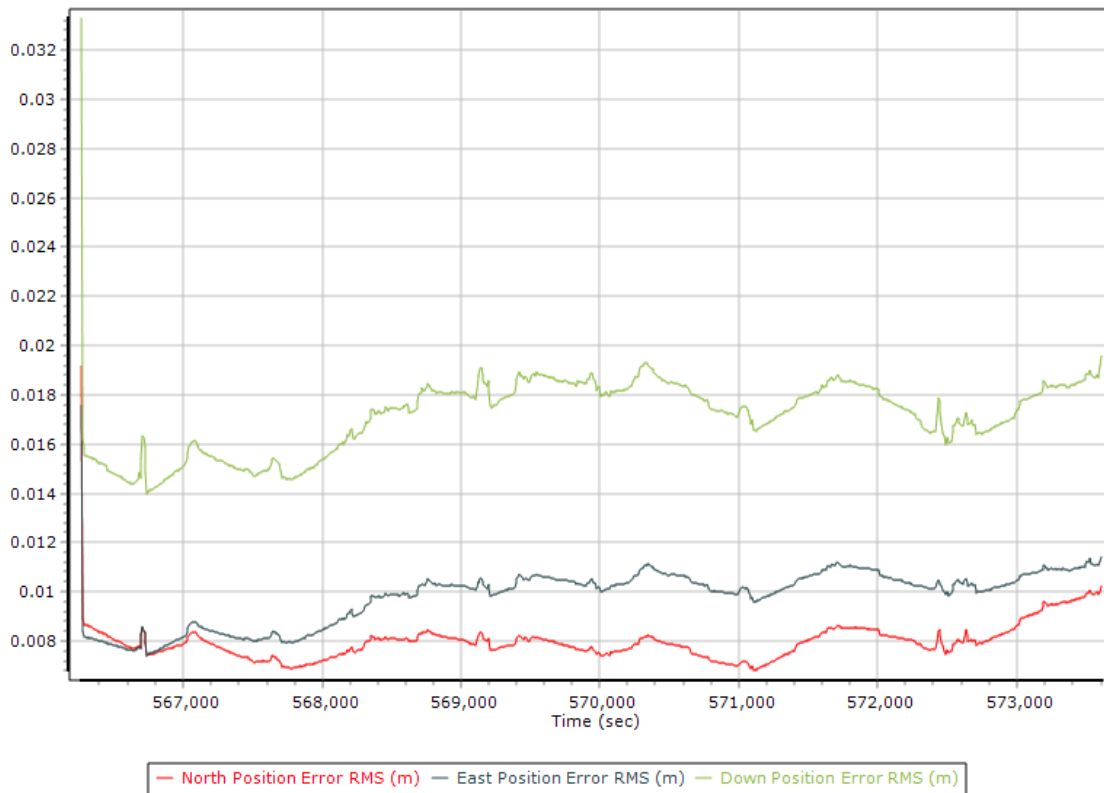
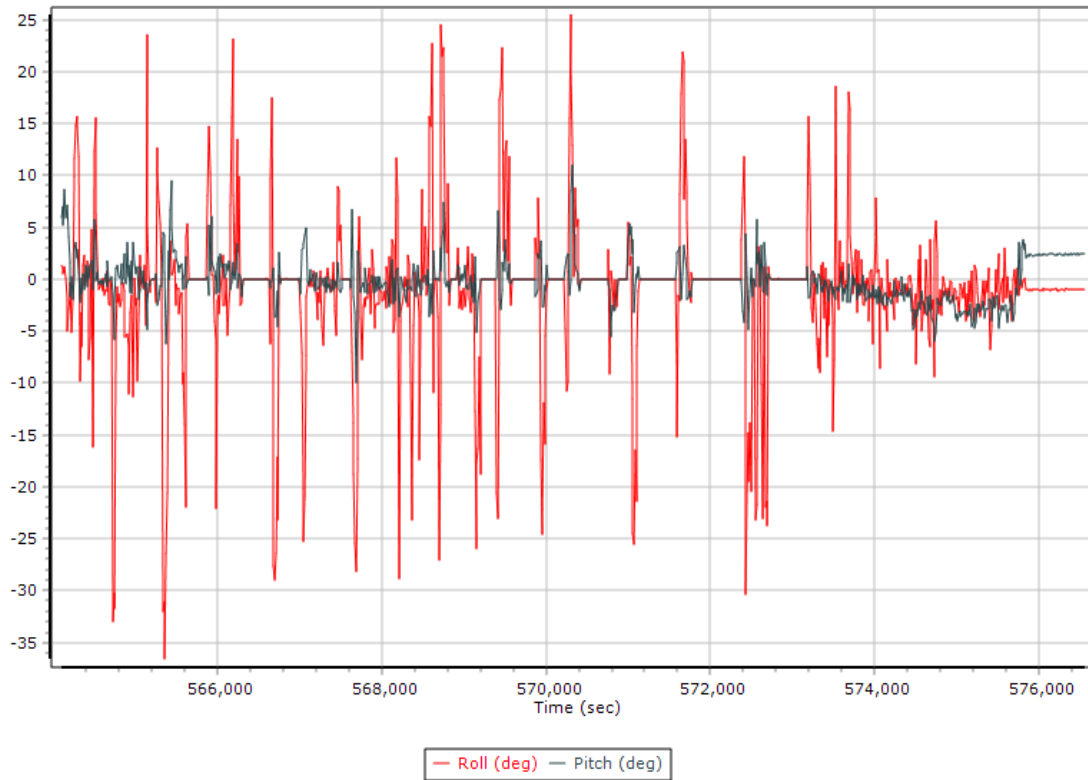
Entire time interval

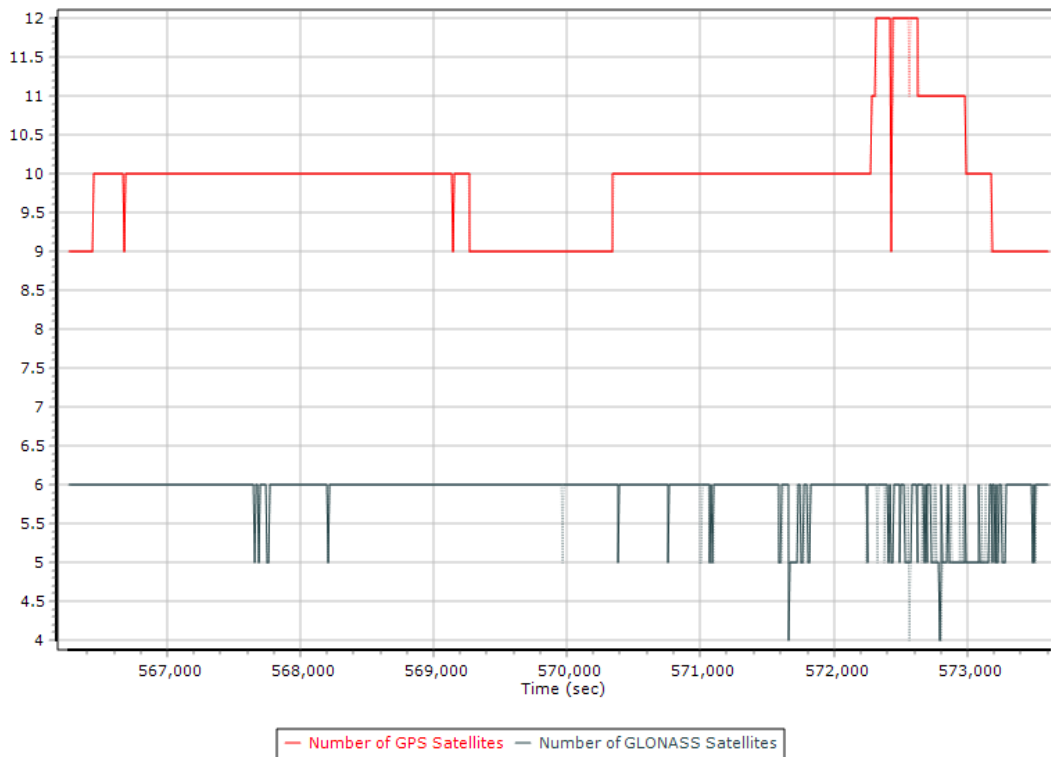
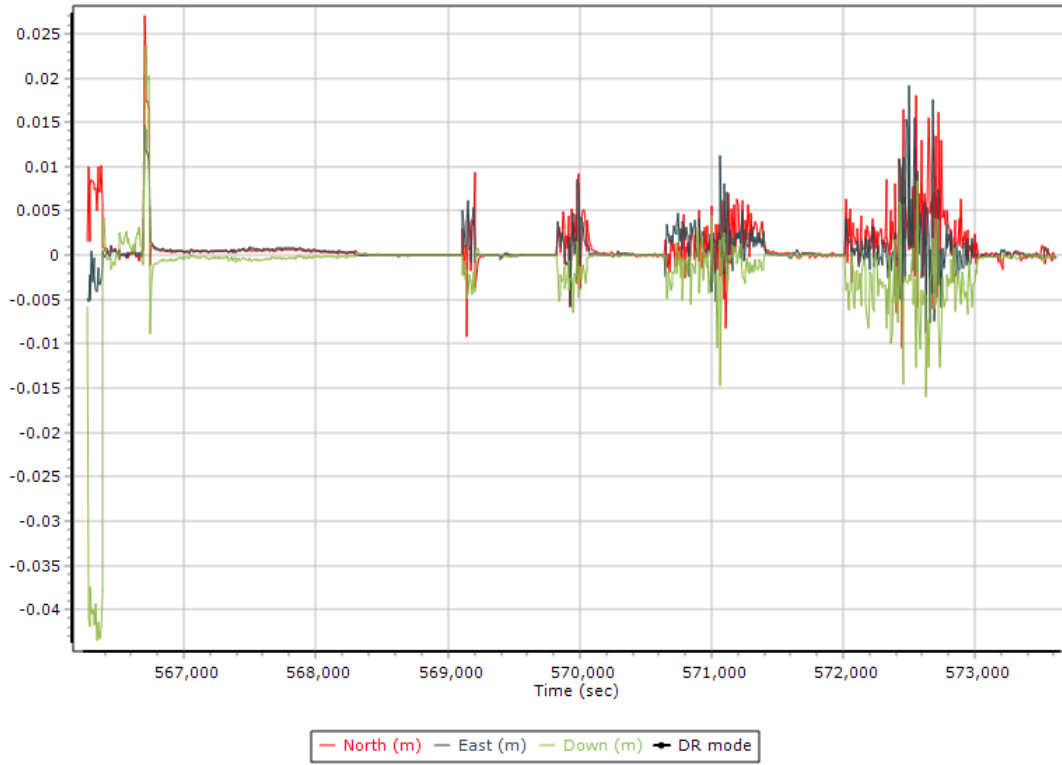
Seconds of start week

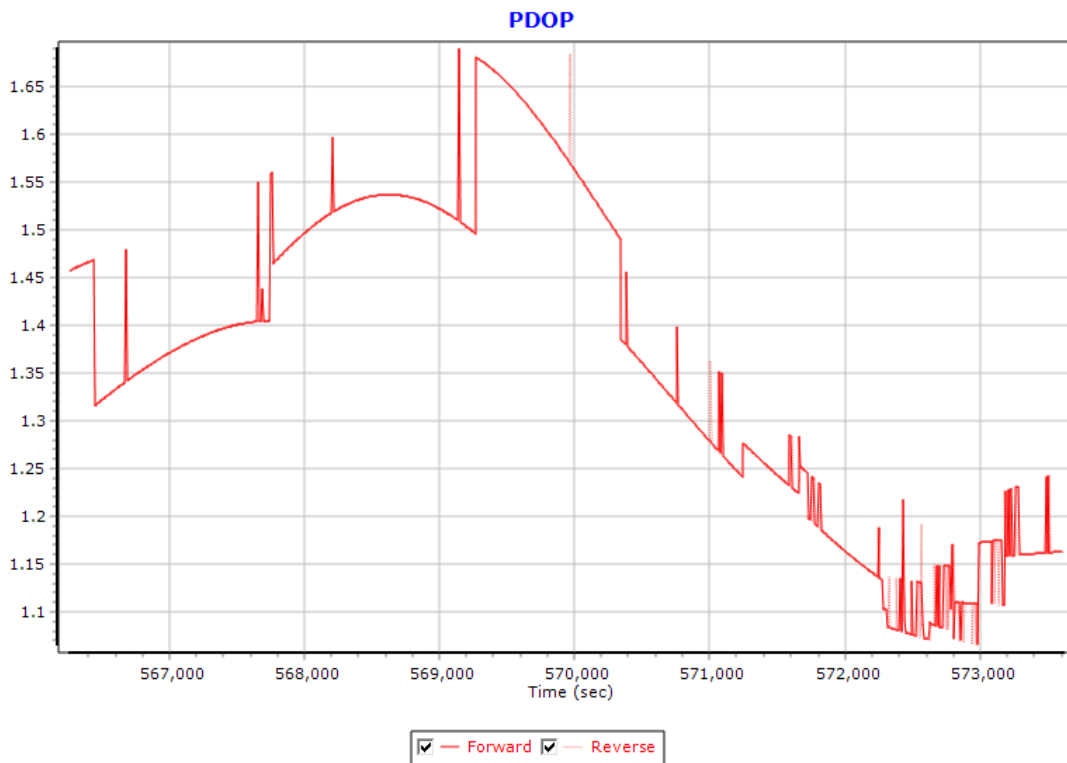
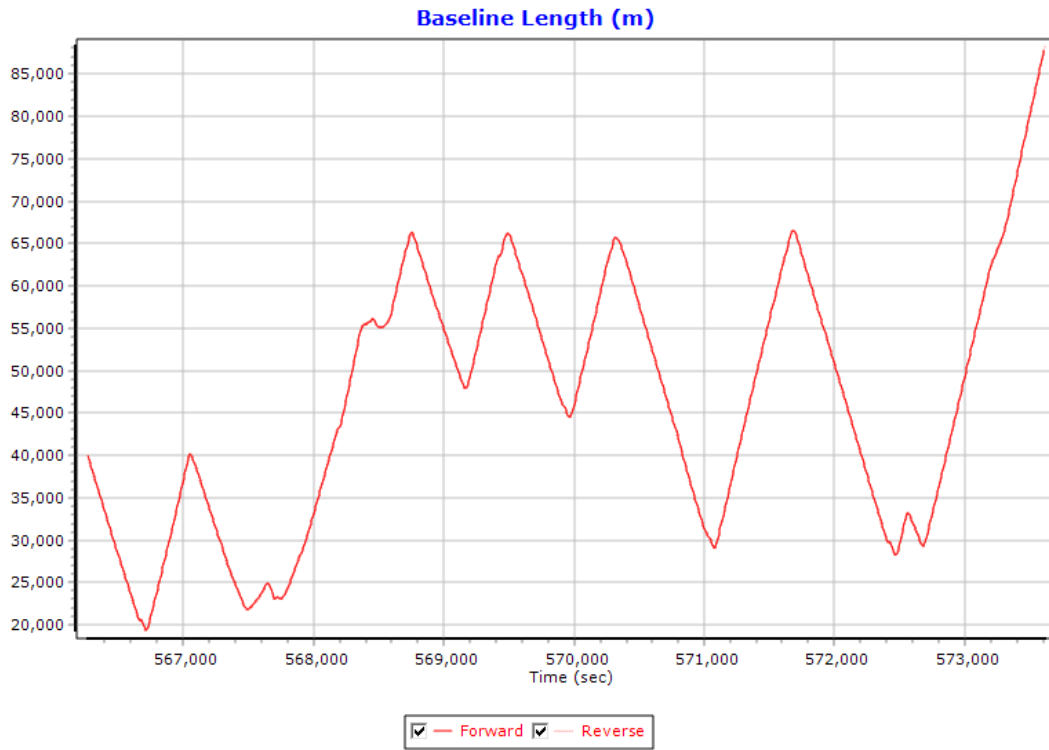
UTC Offset

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

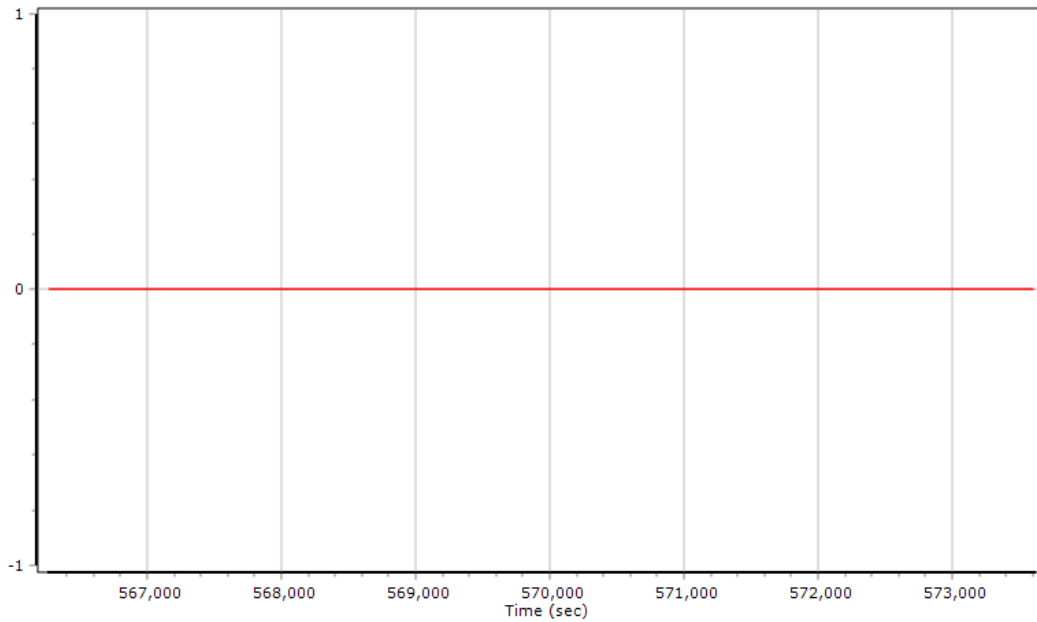








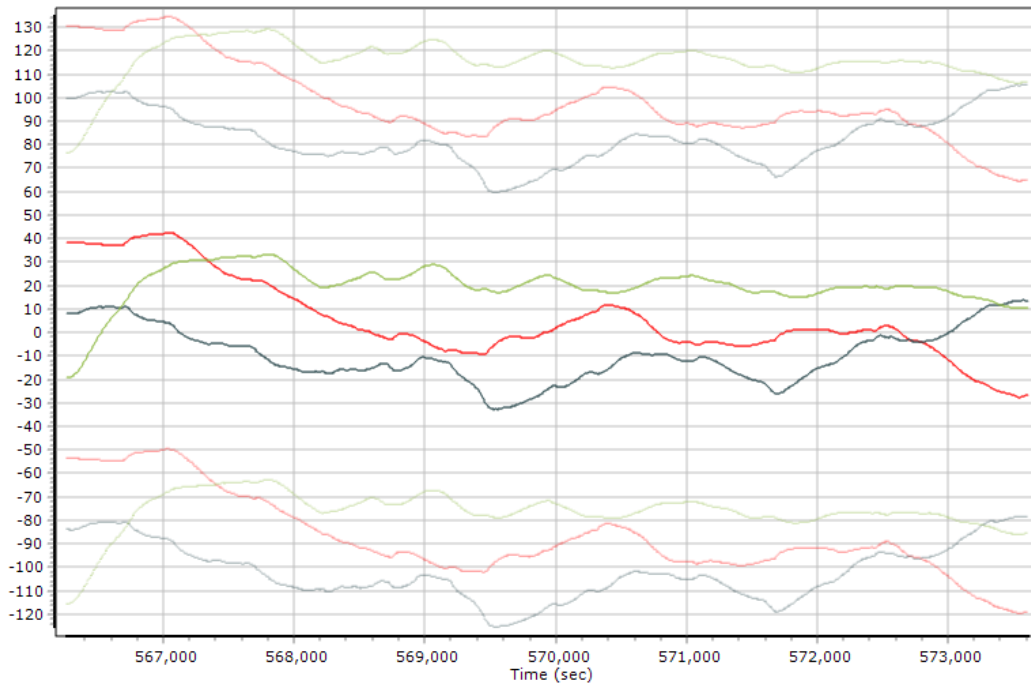
Processing mode



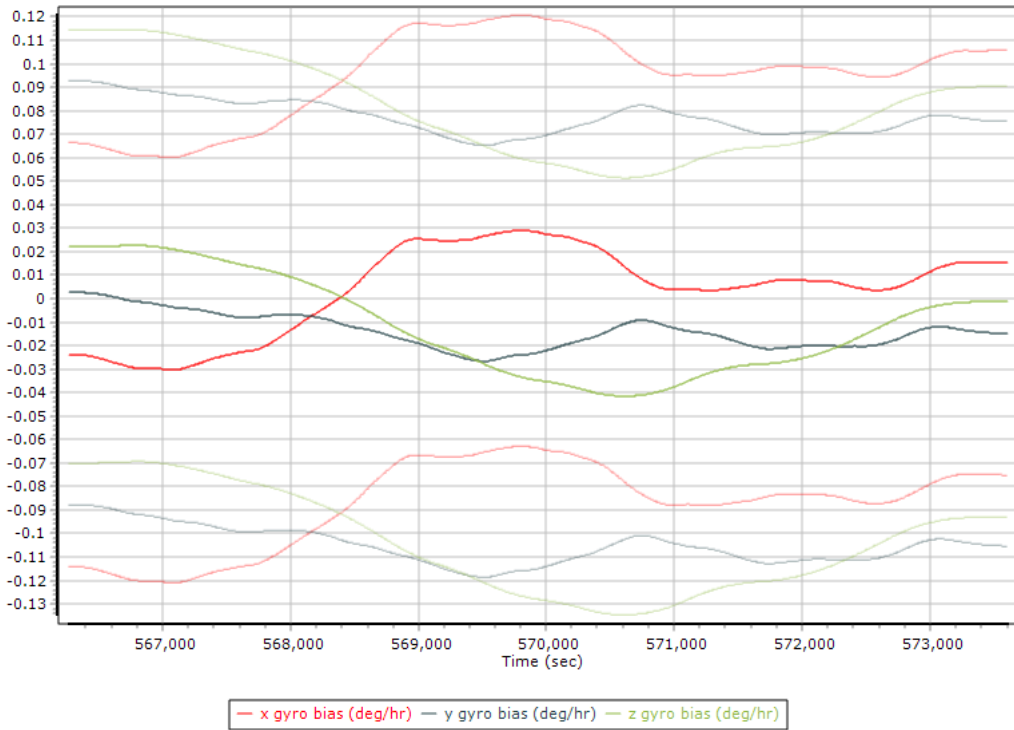
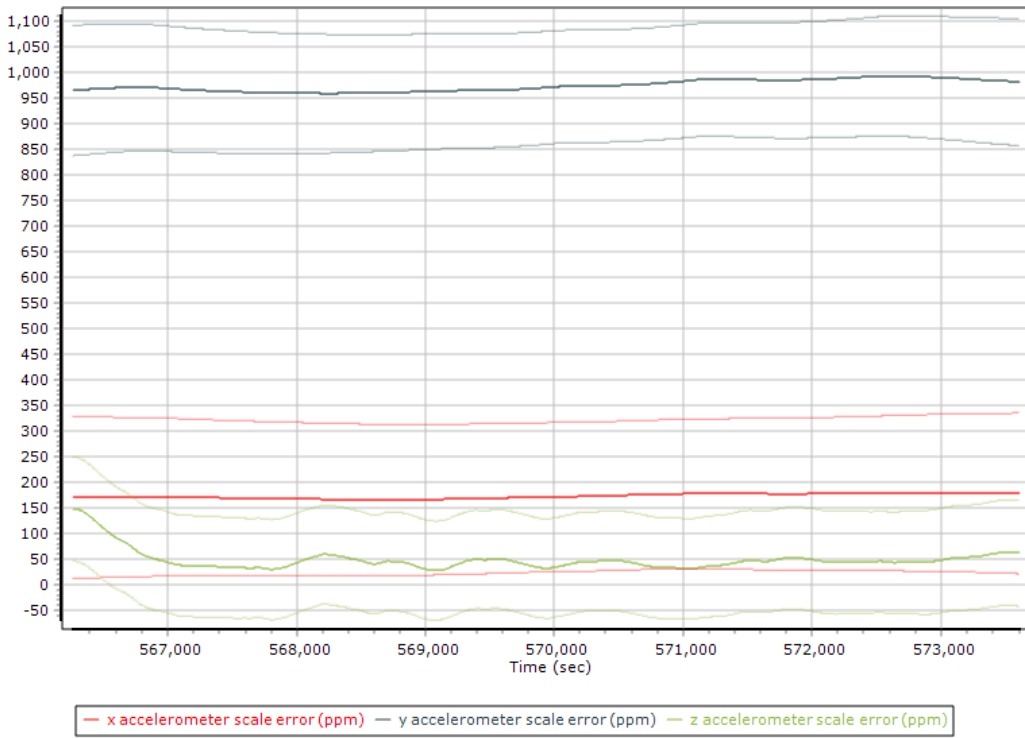
Forward Reverse

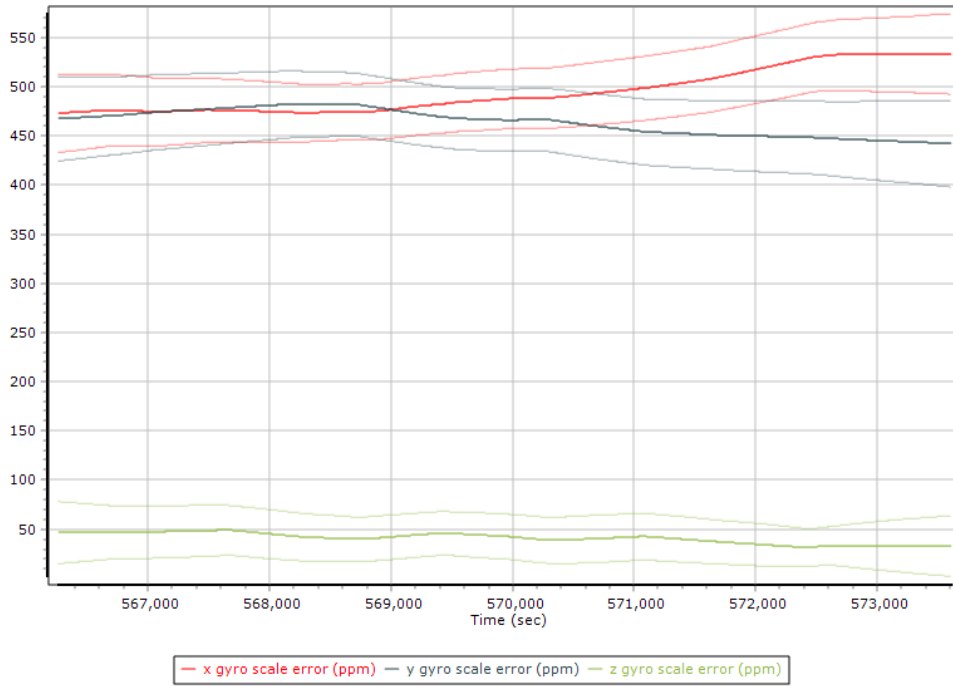
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

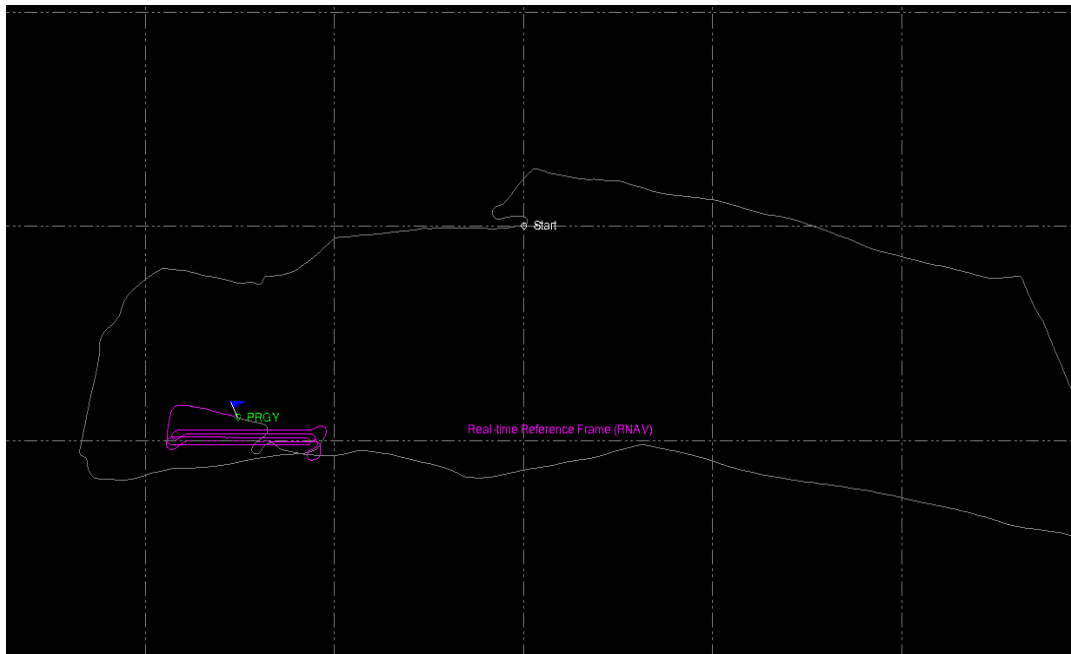


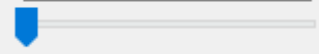
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



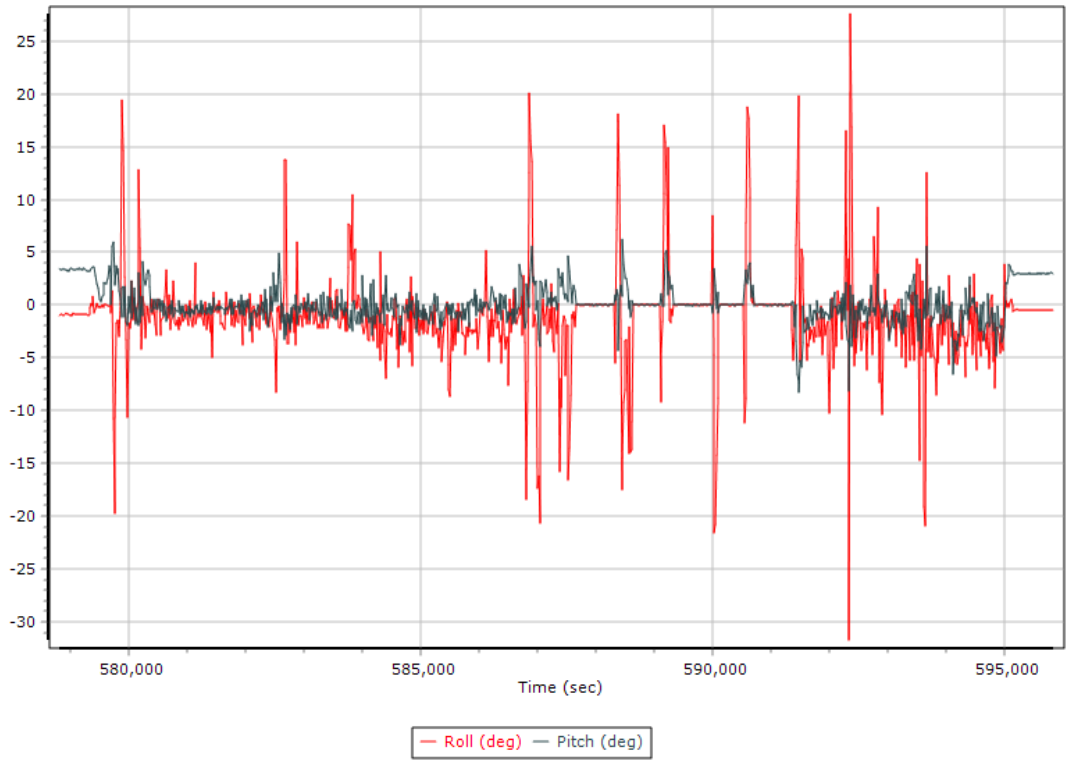
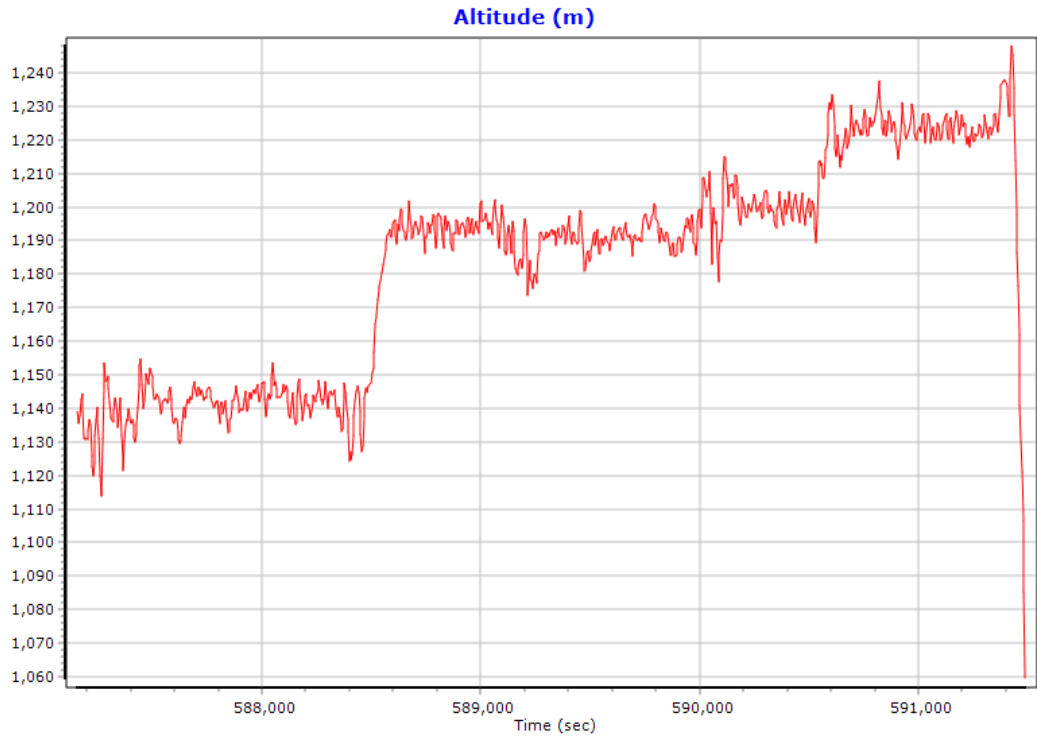


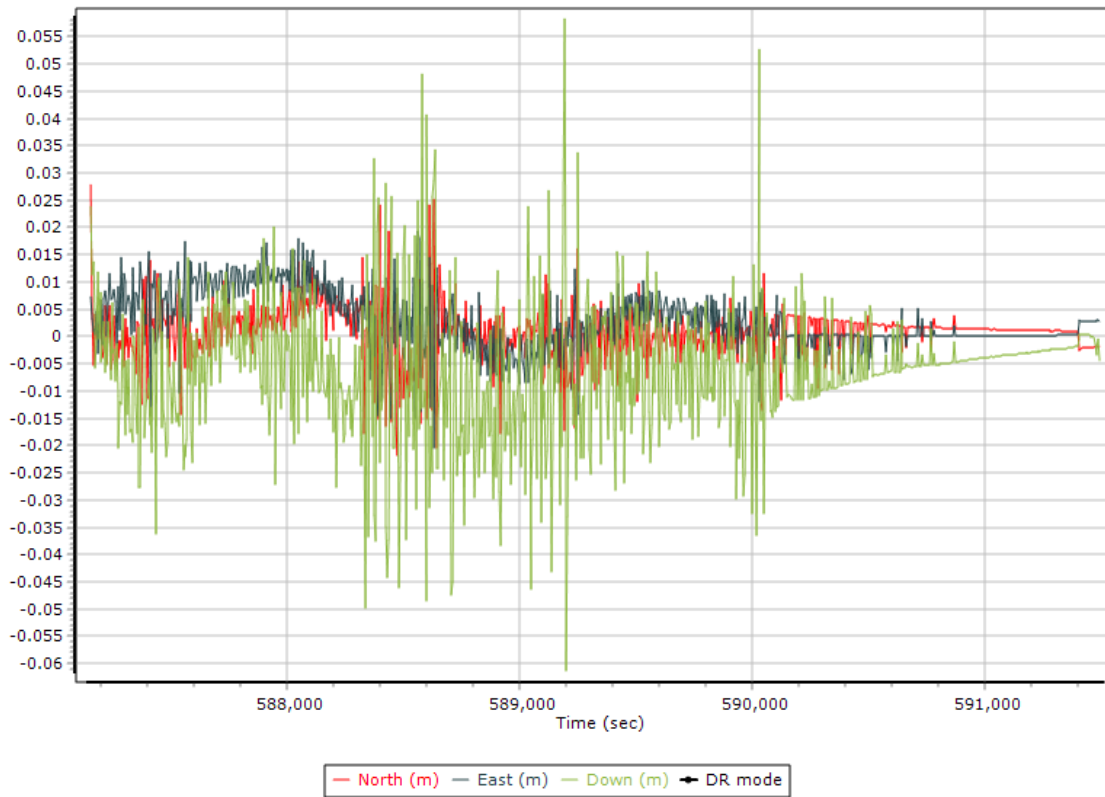
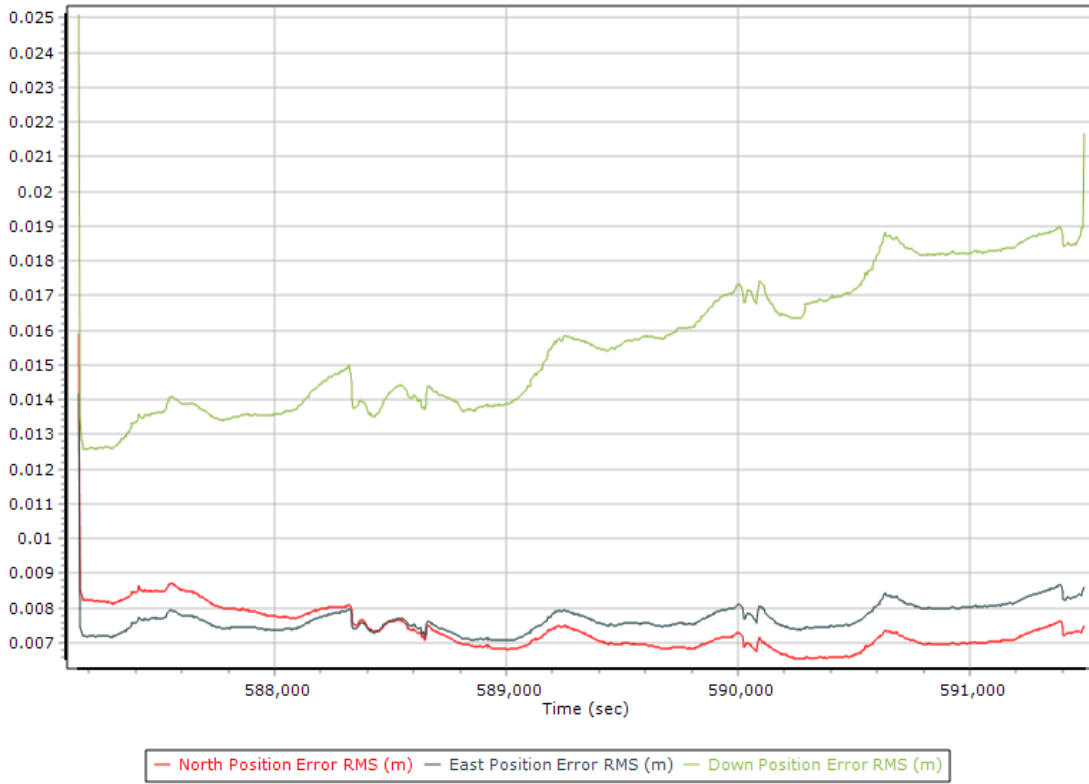
AZT18139B

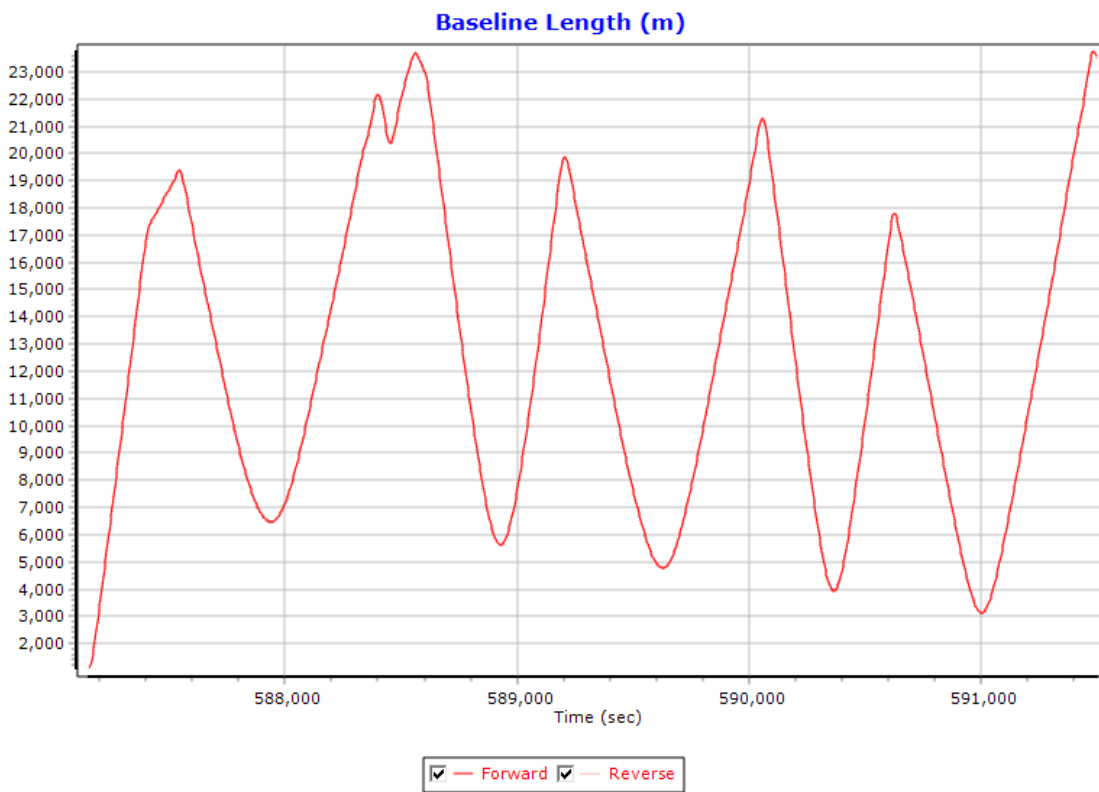
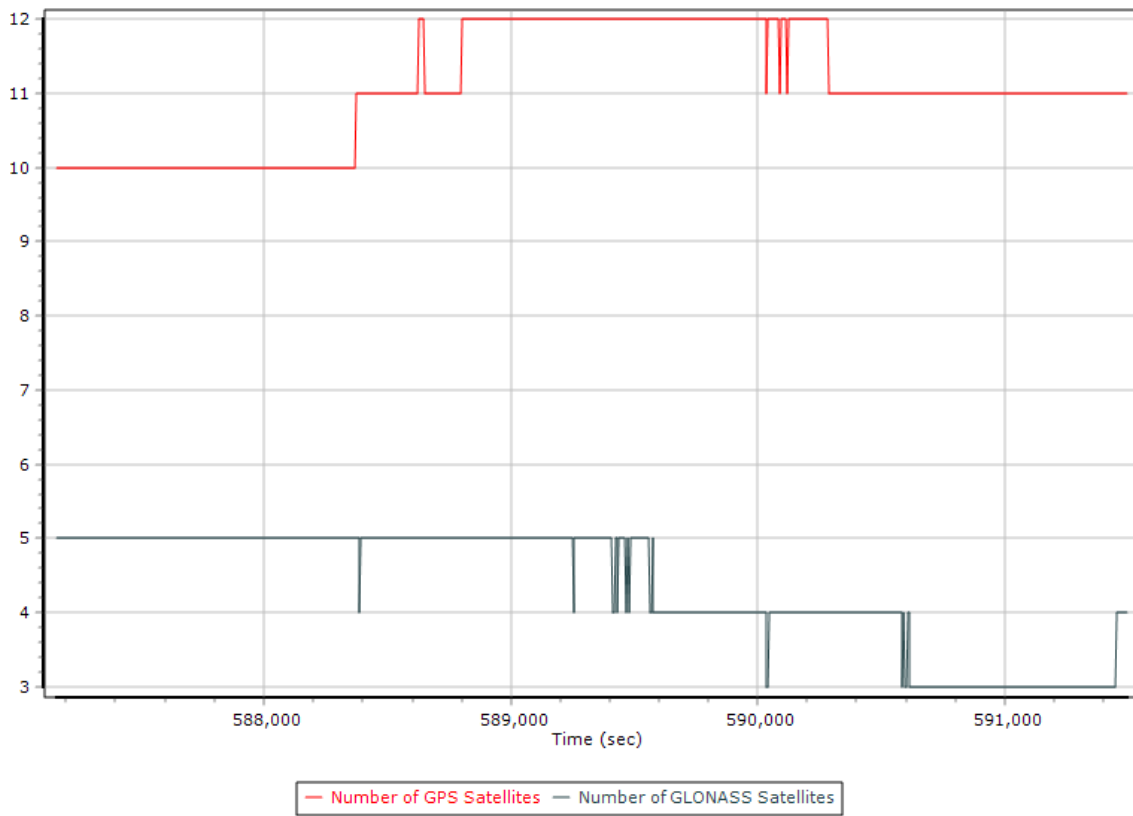


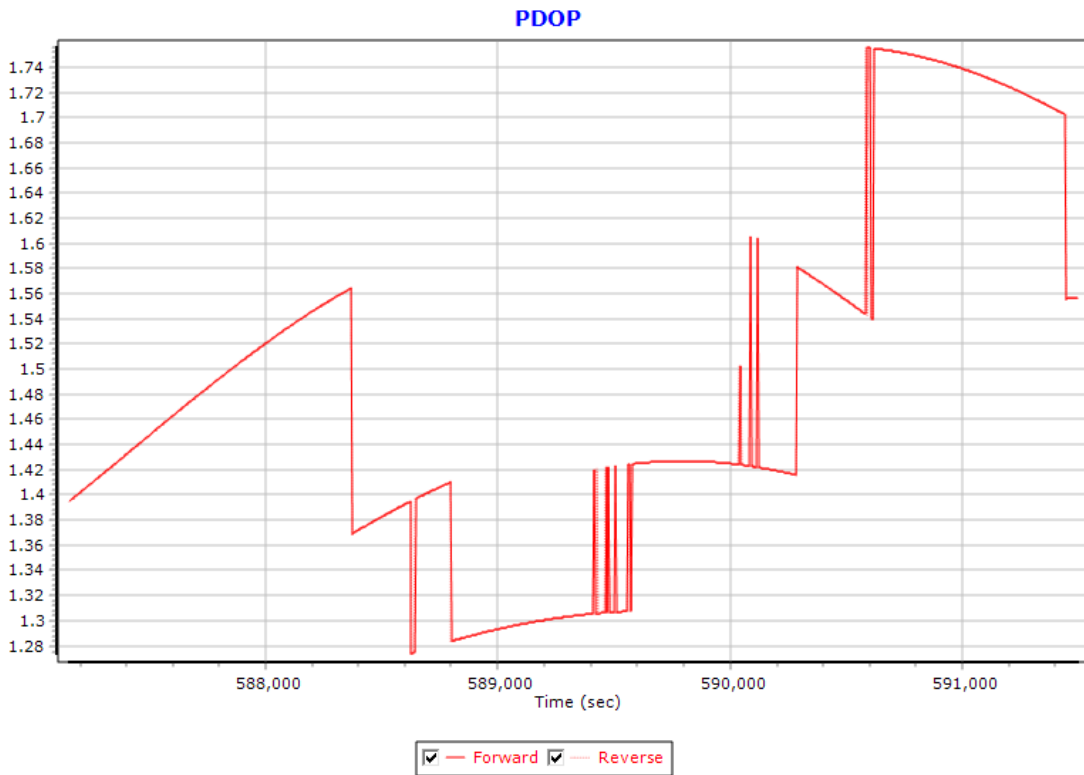
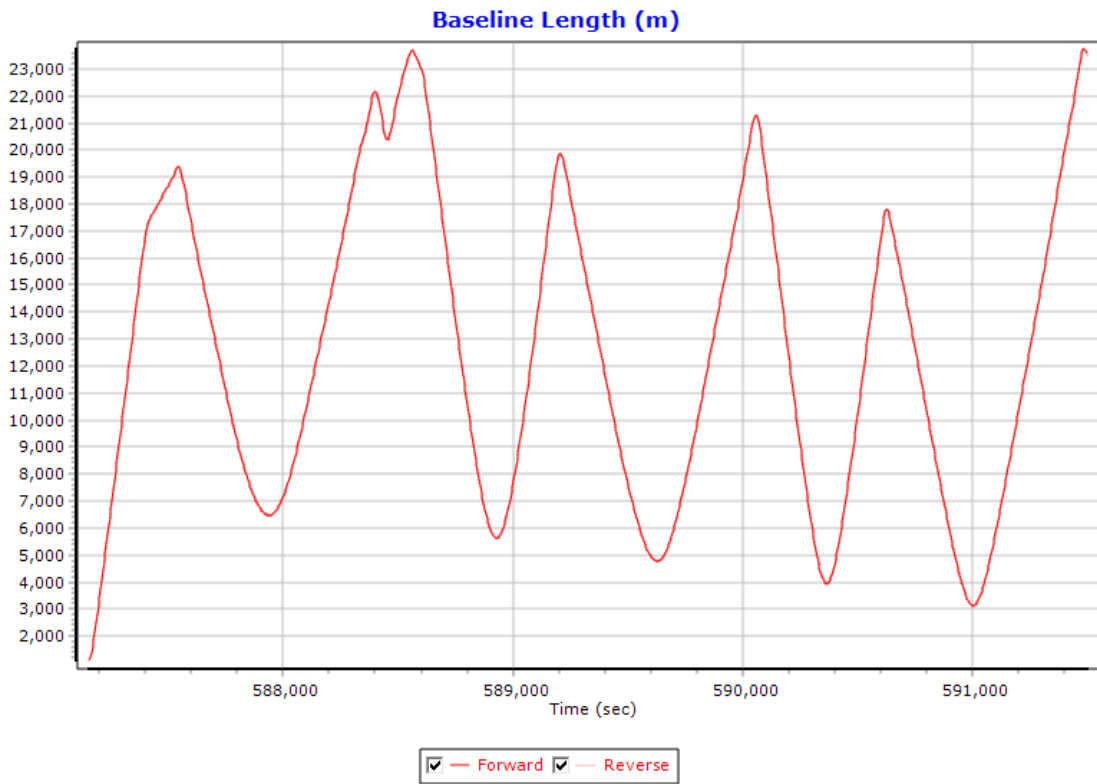
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000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

Timing									
Start	<input type="text" value="587154.896"/>								
End	<input type="text" value="591498.912"/>								
<input type="checkbox"/> Entire time interval									
<input checked="" type="checkbox"/> Seconds of start week									
UTC Offset	<input type="text" value="18.000"/>								
<table border="1"><thead><tr><th>Data</th><th>Incr. (sec)</th></tr></thead><tbody><tr><td>Output Record</td><td>0.005000</td></tr><tr><td>IMU</td><td>0.005000</td></tr><tr><td>Primary GNSS</td><td>1.000000</td></tr></tbody></table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000	<input type="button" value="Up"/> <input type="button" value="Down"/>
Data	Incr. (sec)								
Output Record	0.005000								
IMU	0.005000								
Primary GNSS	1.000000								

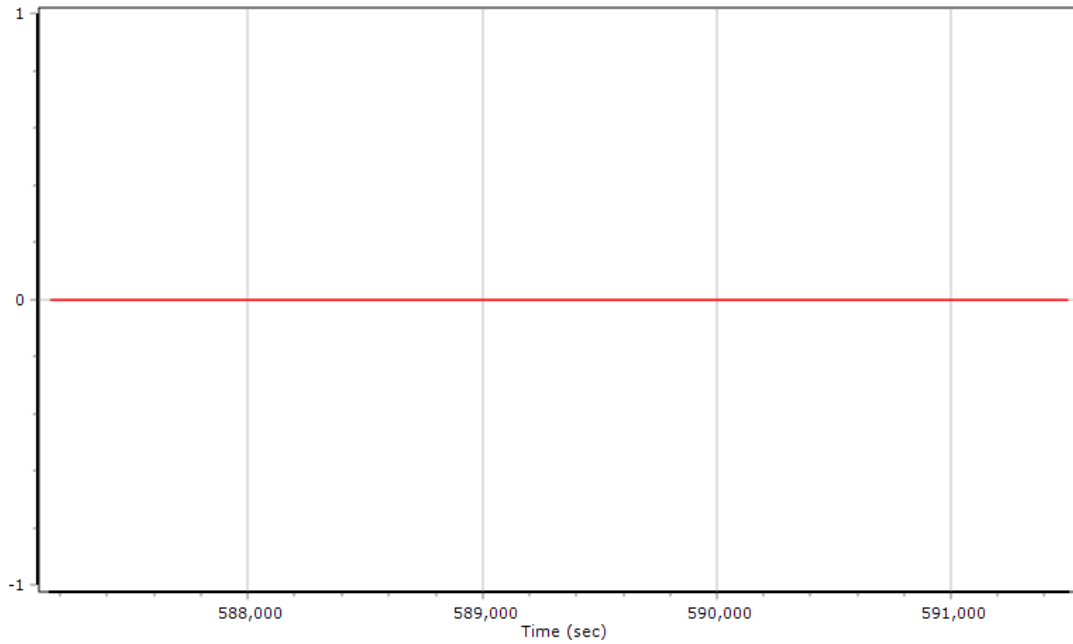








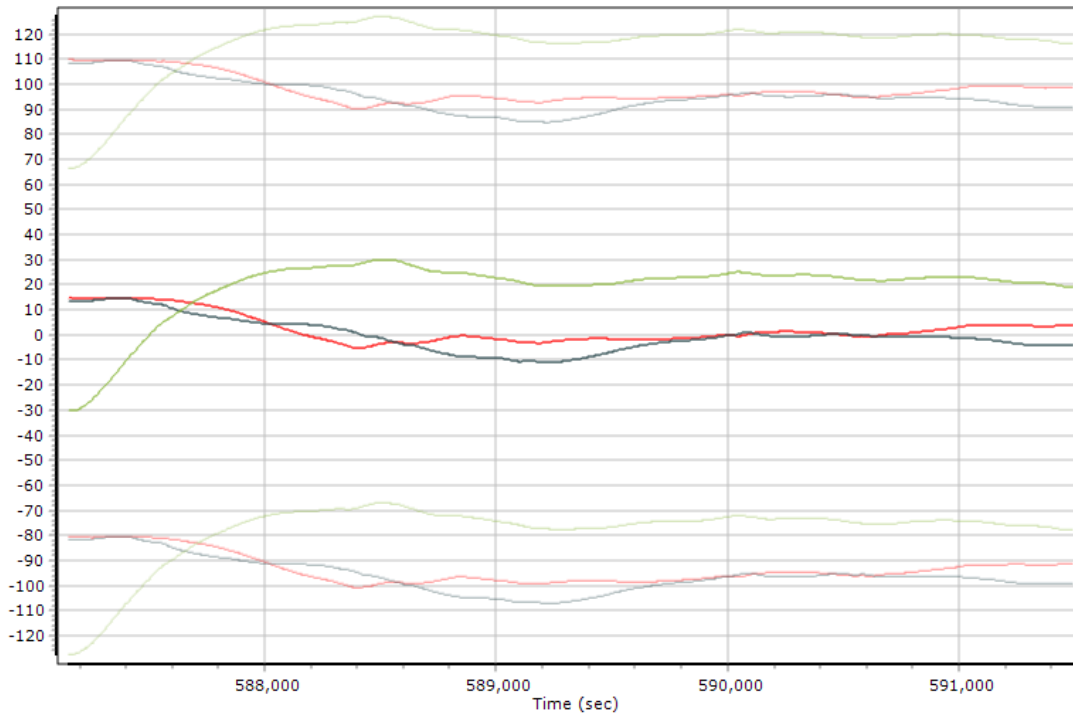
Processing mode



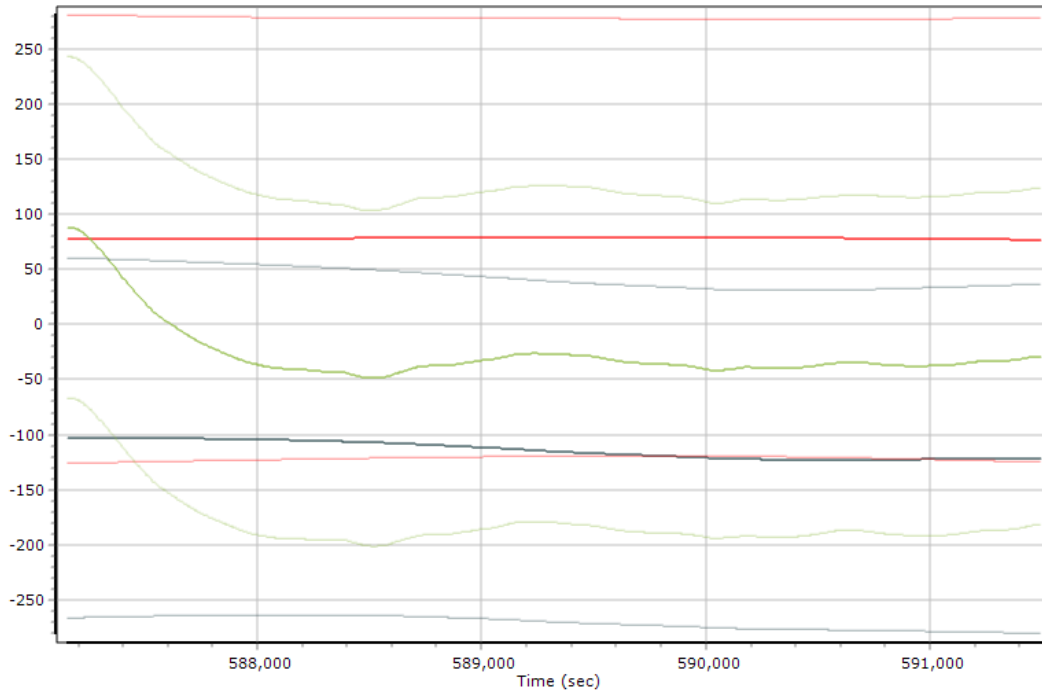
Forward Reverse

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

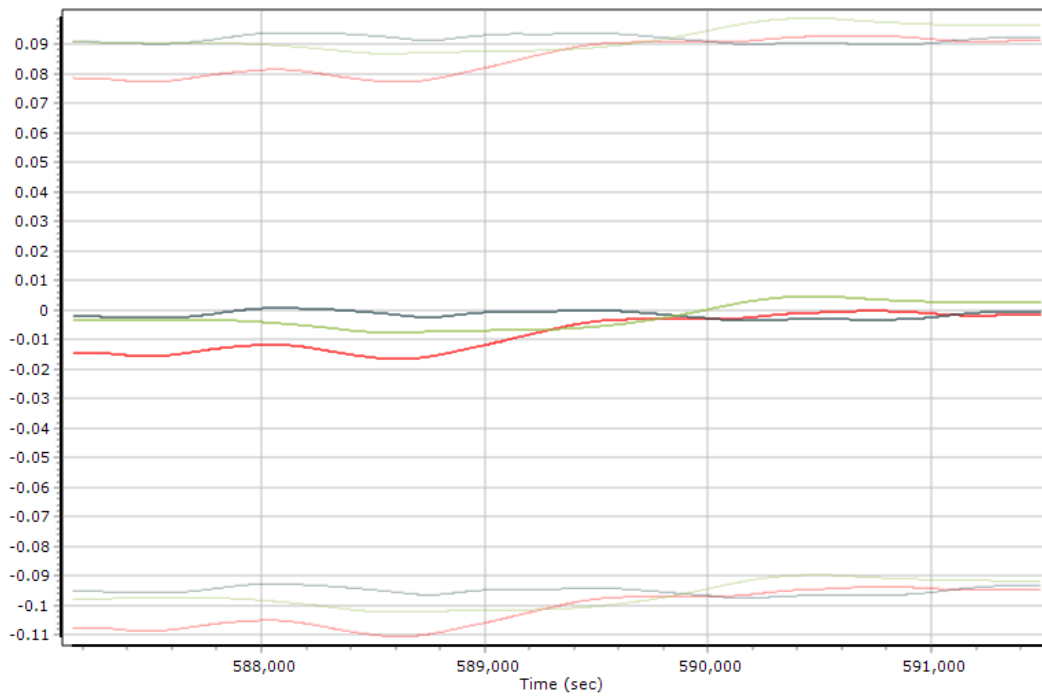
Sensor Errors



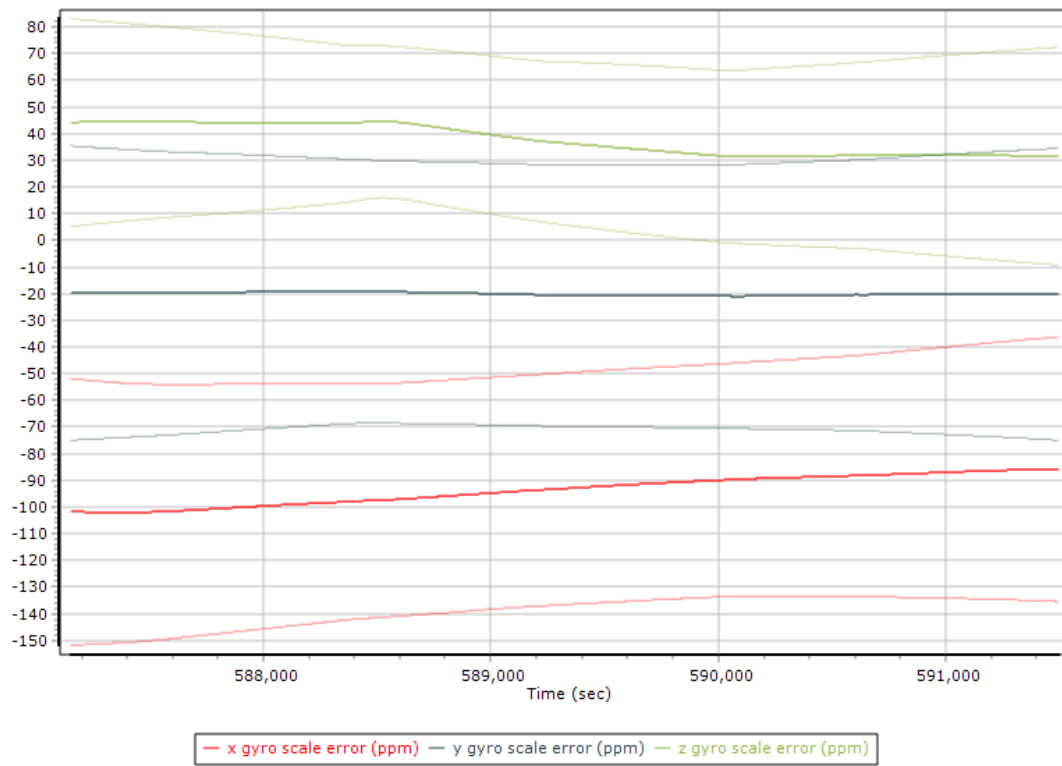
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



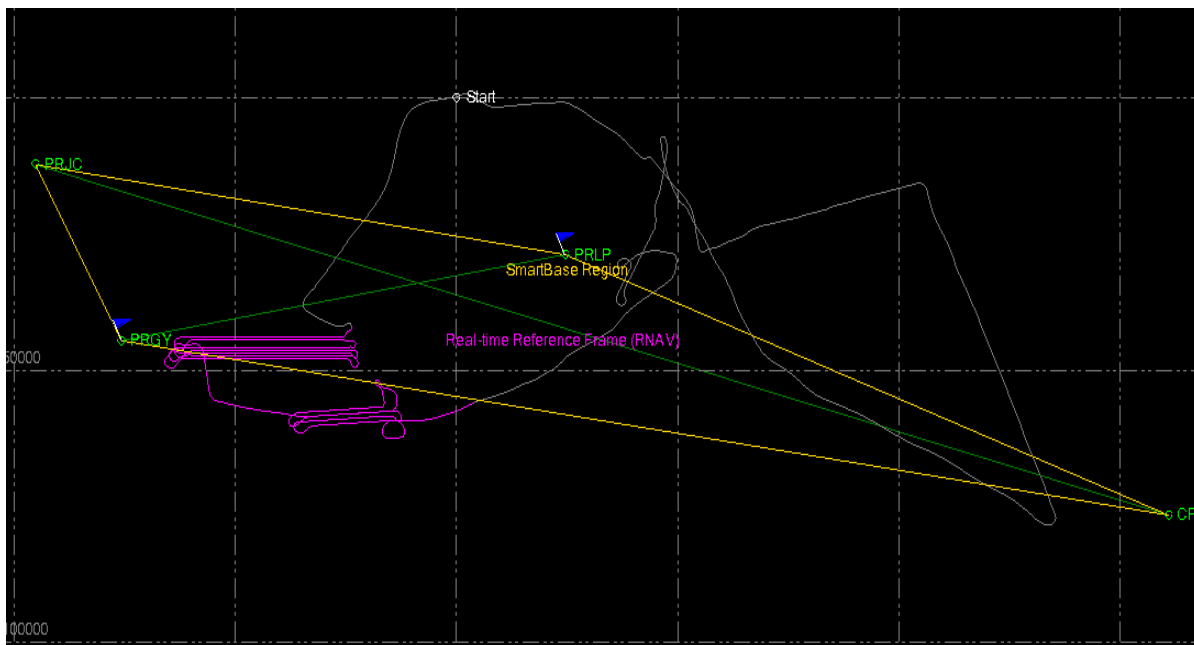
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



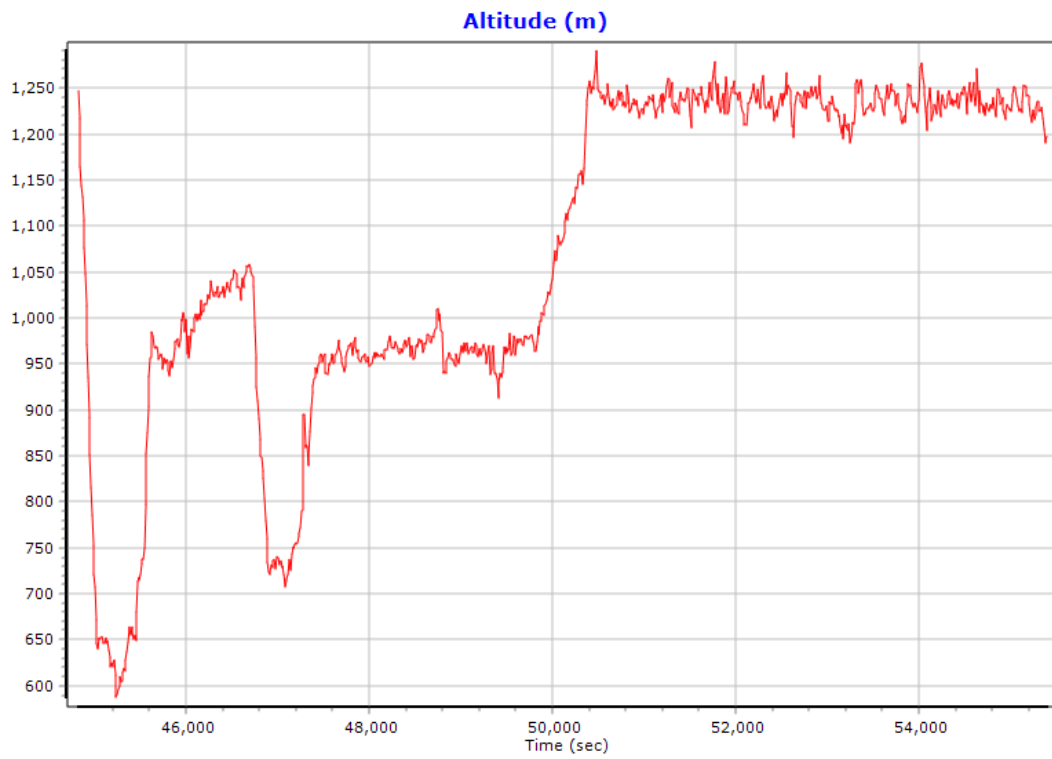
AZT18140A



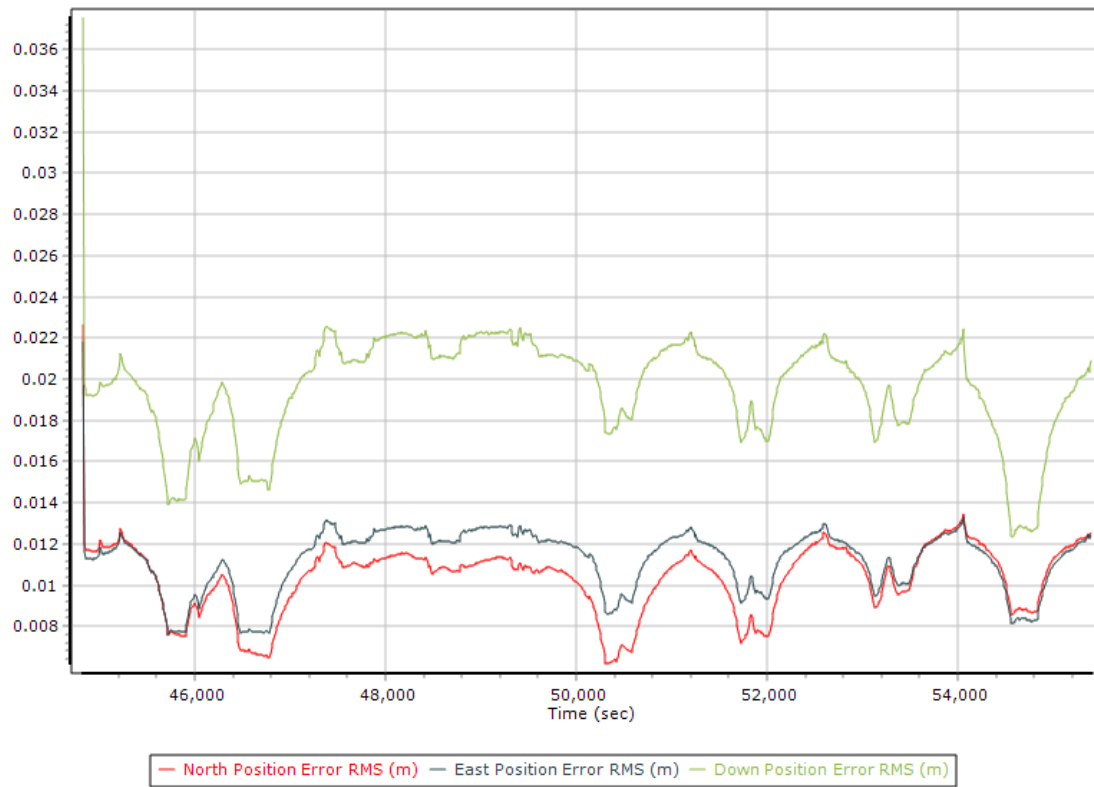
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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 max="10" min="0.01" type="range" value="0.03"/>		
	<small><3cm 10cm 50cm 1m 10m</small>		

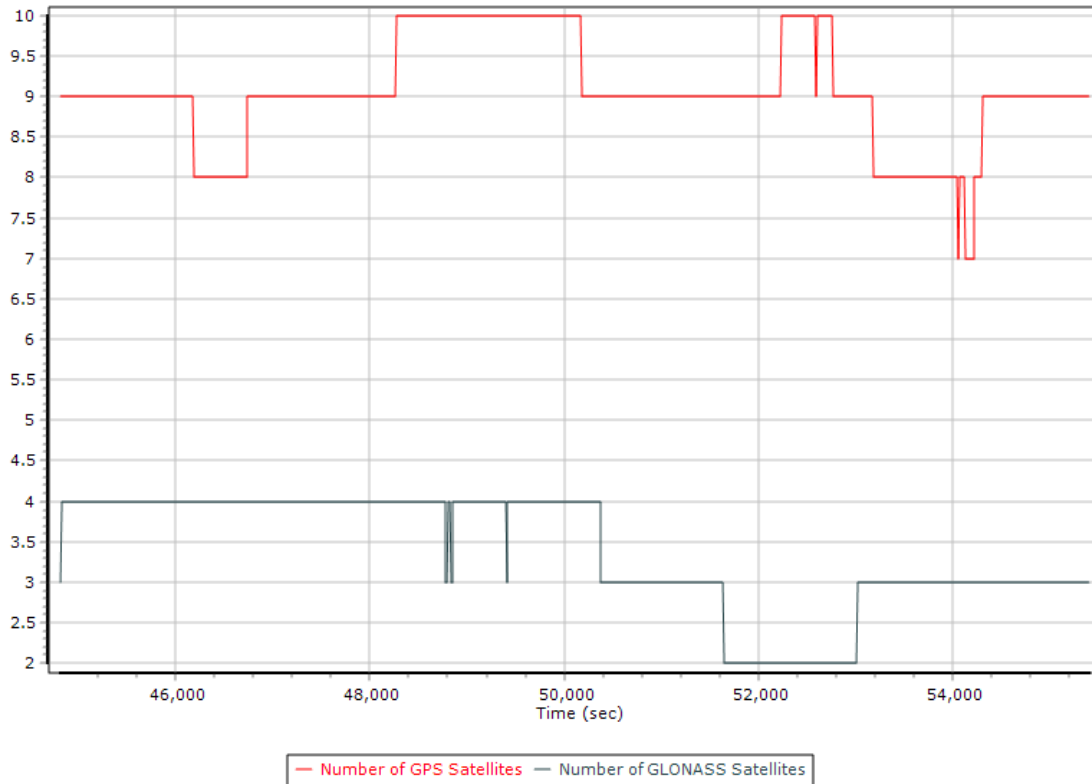
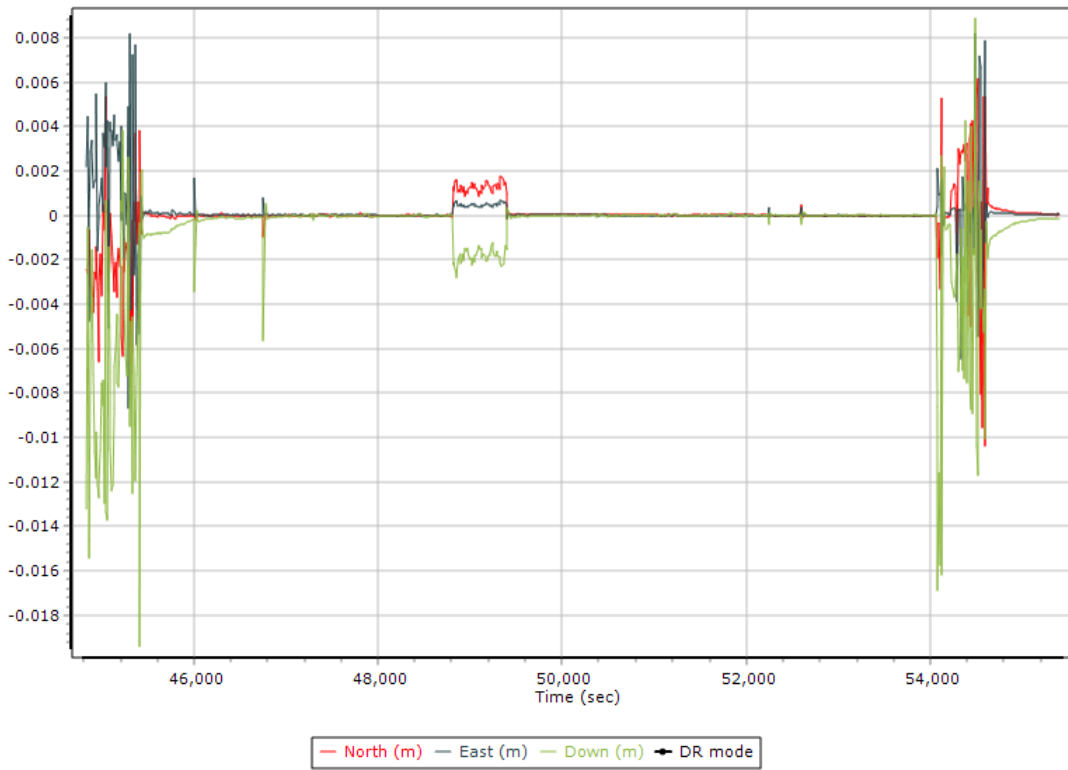
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

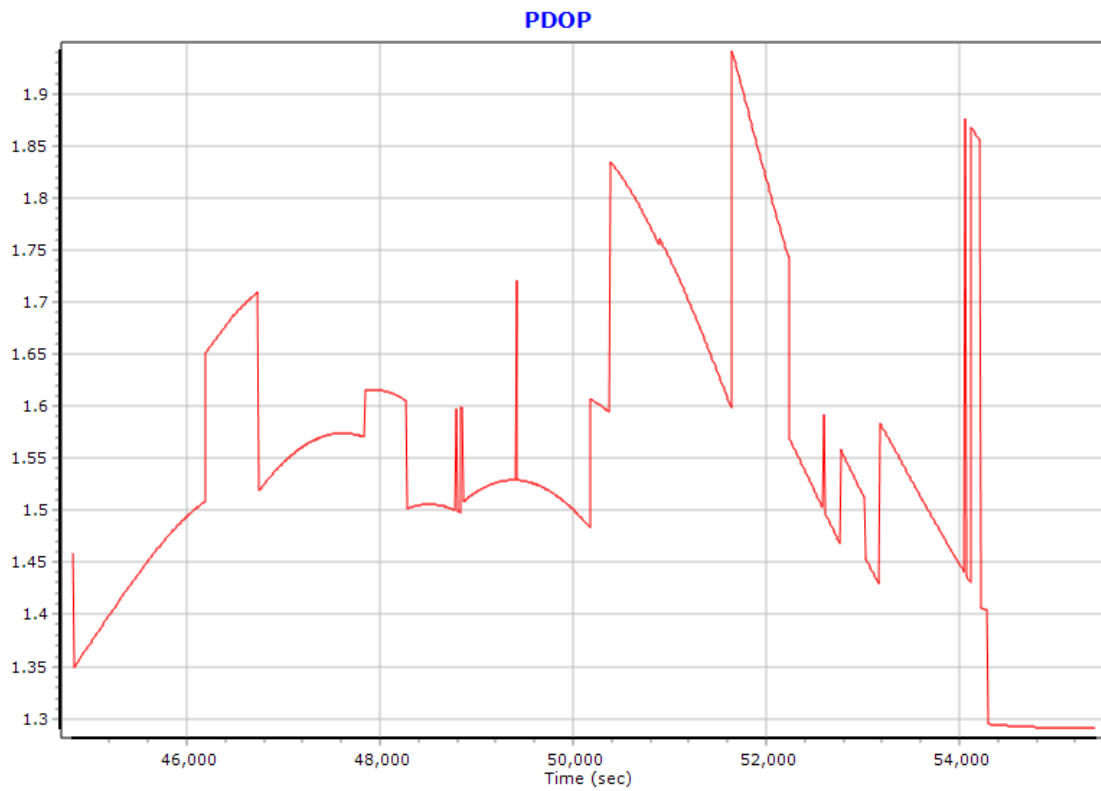
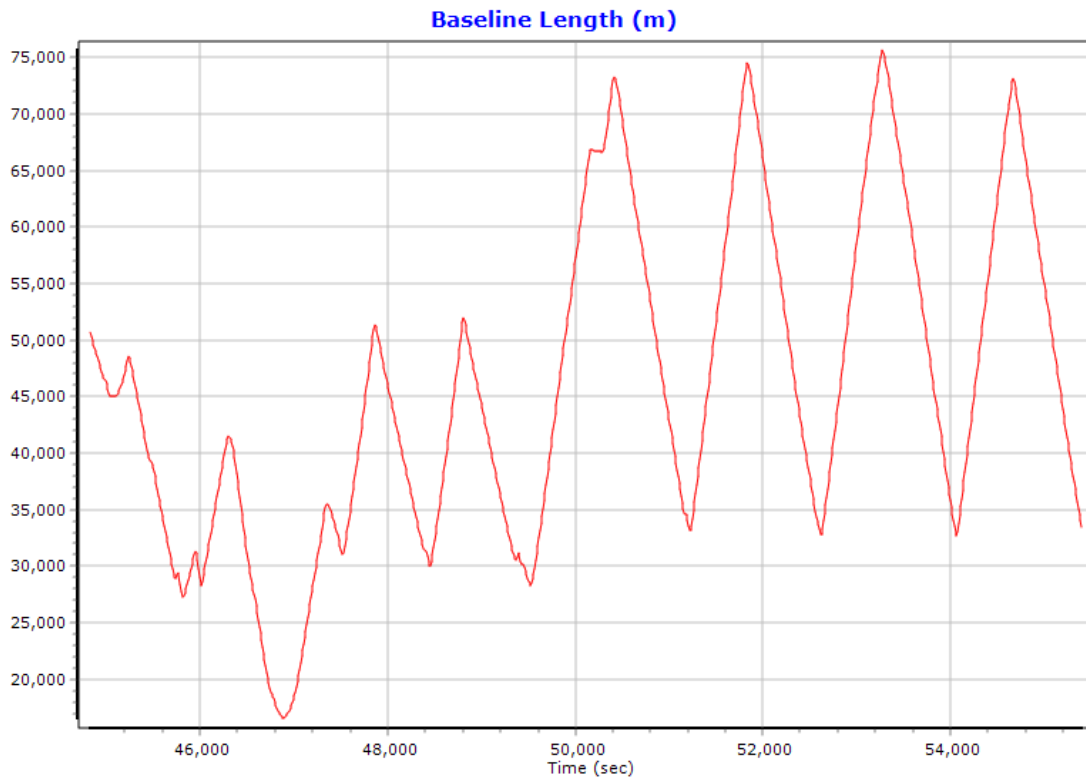
Timing									
Start	<input type="text" value="44821.784"/>								
End	<input type="text" value="55414.274"/>								
<input type="checkbox"/> Entire time interval									
<input checked="" type="checkbox"/> Seconds of start week									
UTC Offset	<input type="text" value="18.000"/>								
<table border="1"><thead><tr><th>Data</th><th>Incr. (sec)</th></tr></thead><tbody><tr><td>Output Record</td><td>0.005000</td></tr><tr><td>IMU</td><td>0.005000</td></tr><tr><td>Primary GNSS</td><td>1.000000</td></tr></tbody></table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000	<input type="button" value="↑"/> <input type="button" value="↓"/>
Data	Incr. (sec)								
Output Record	0.005000								
IMU	0.005000								
Primary GNSS	1.000000								

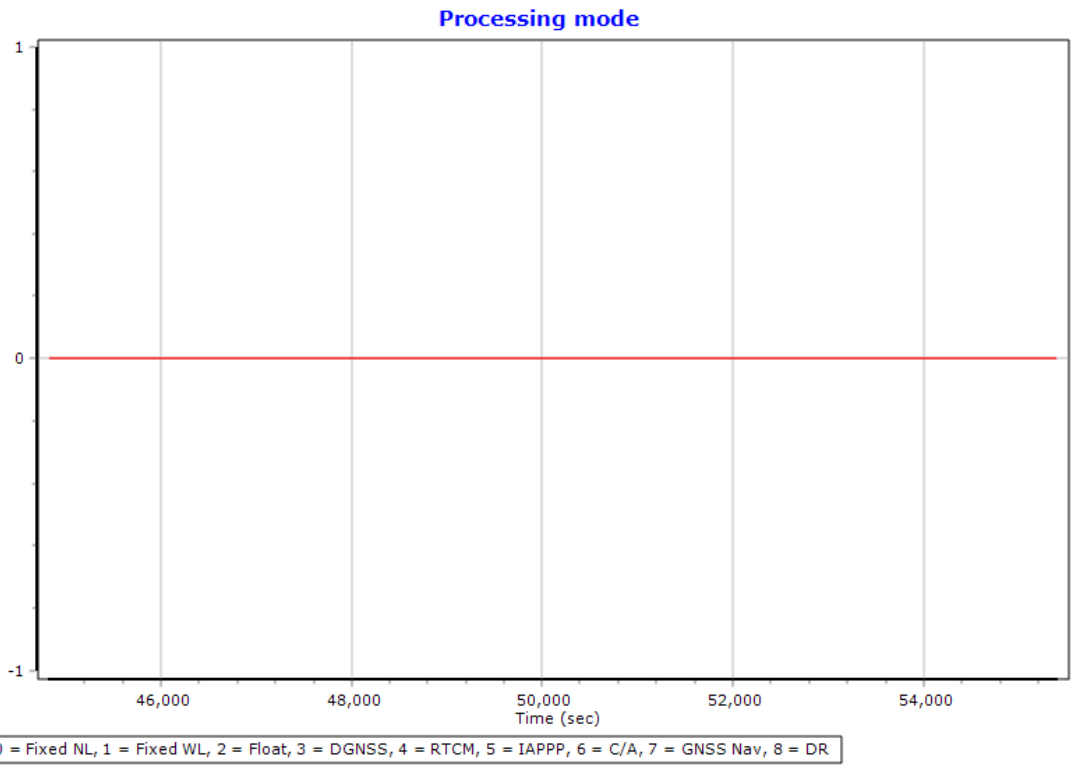


no roll pospac does not open.

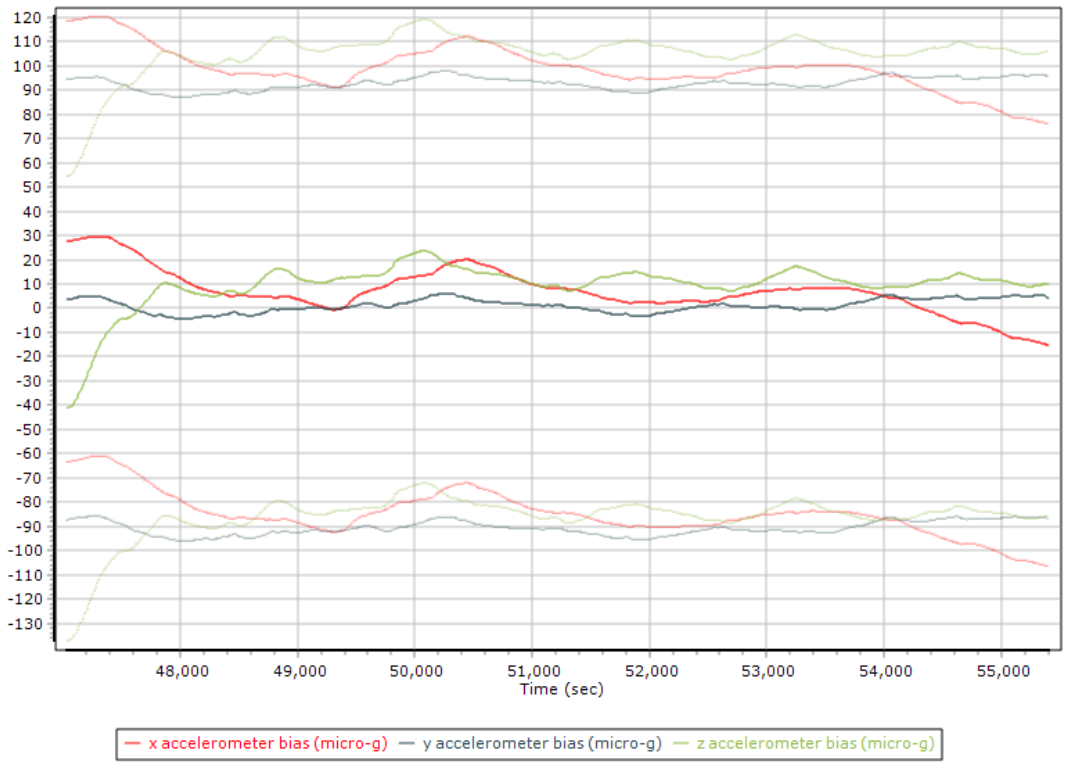


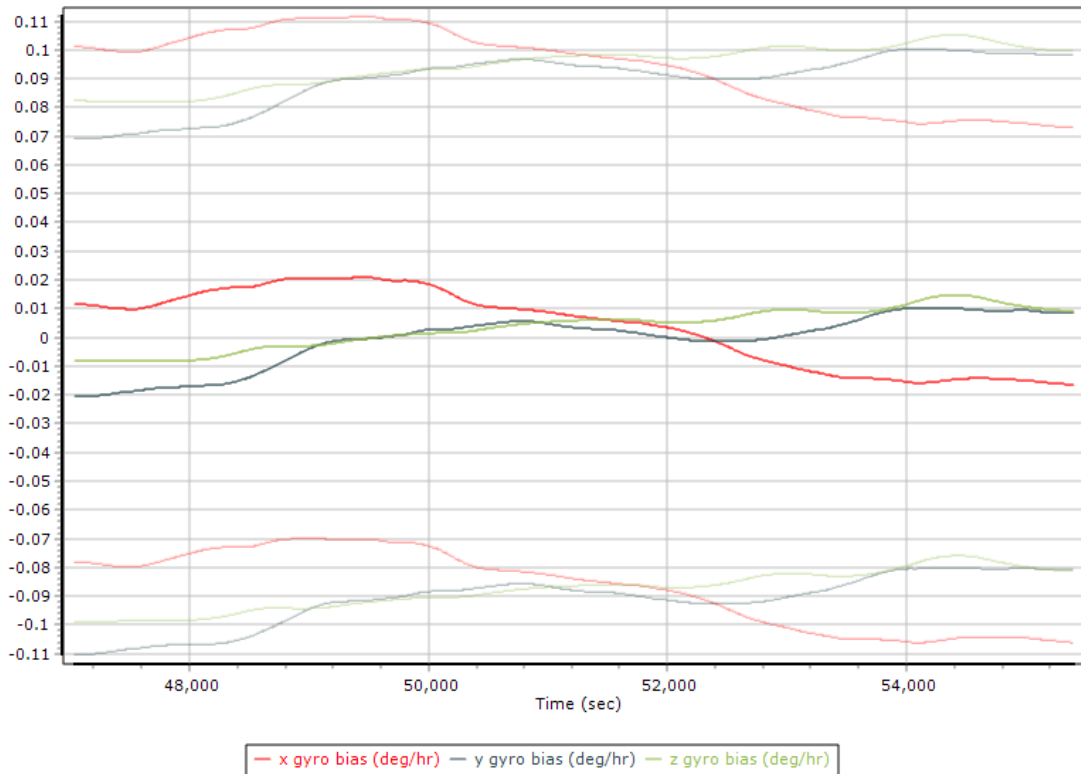
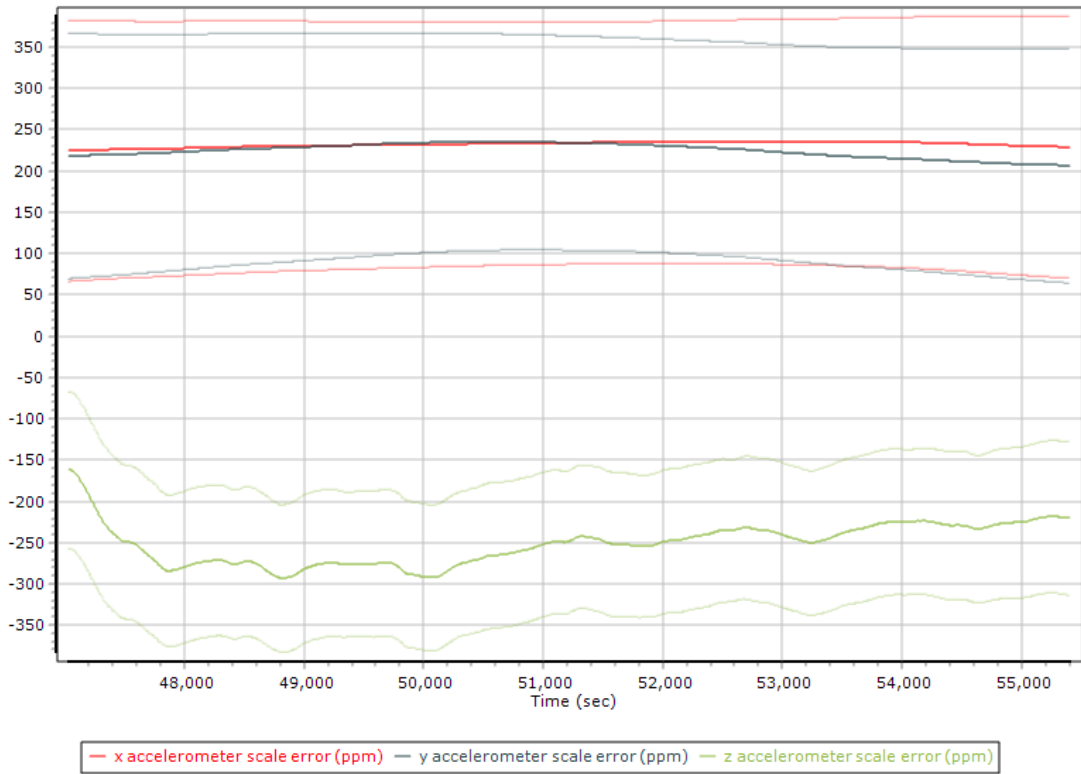


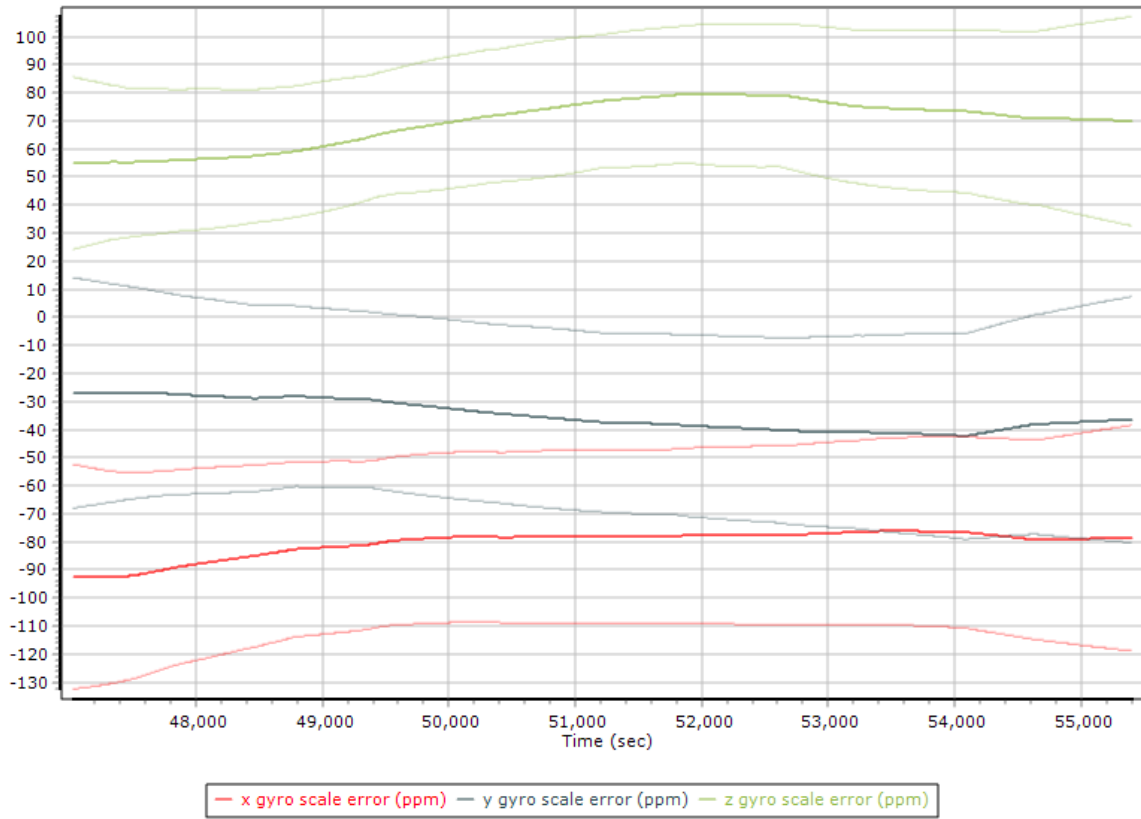




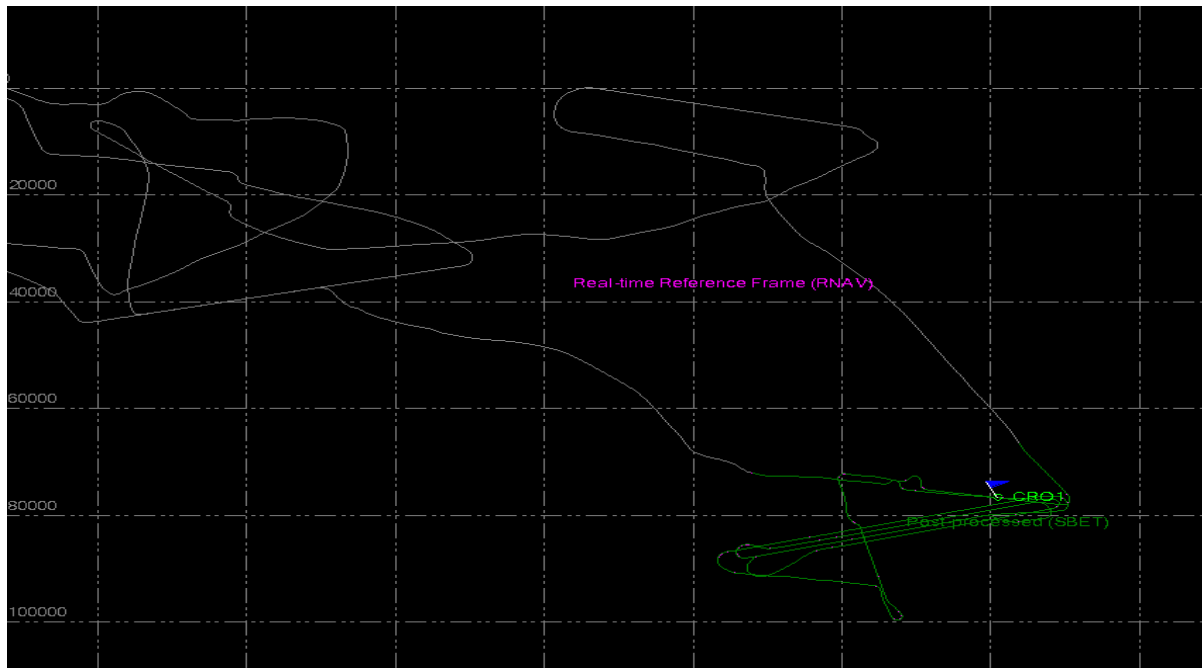
Sensor Errors

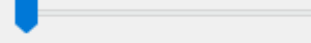







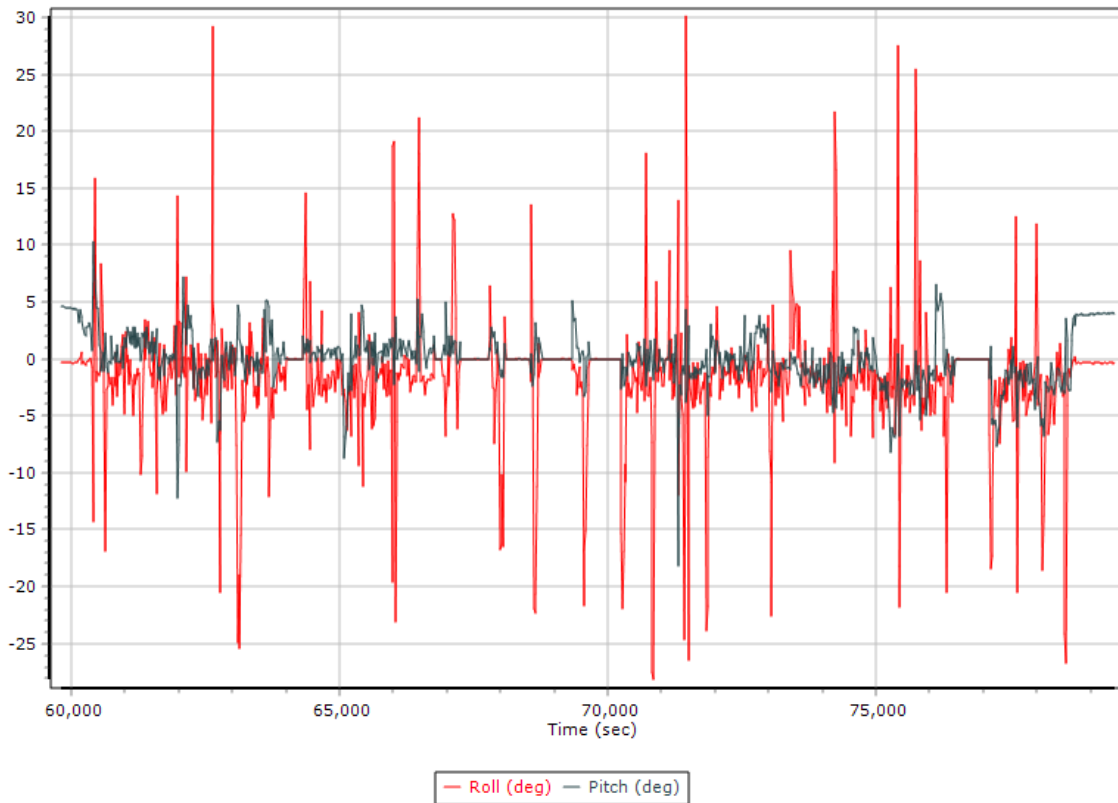
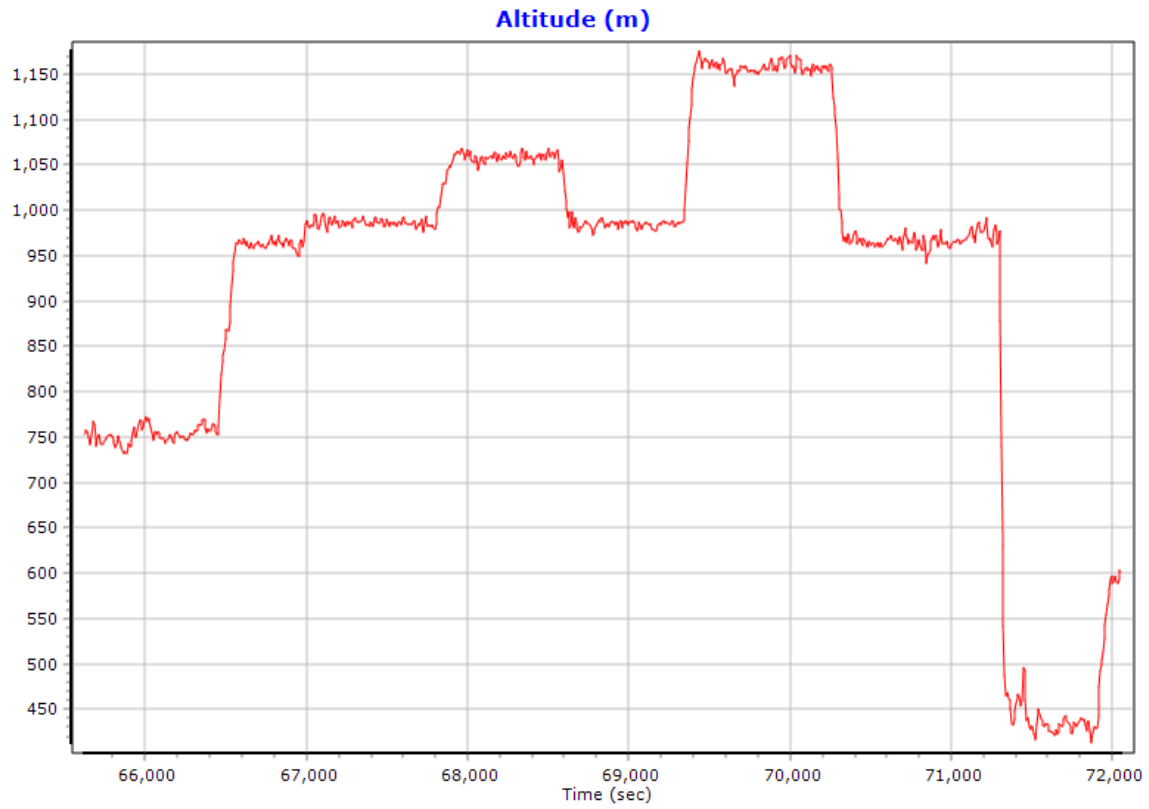
AZT18140B

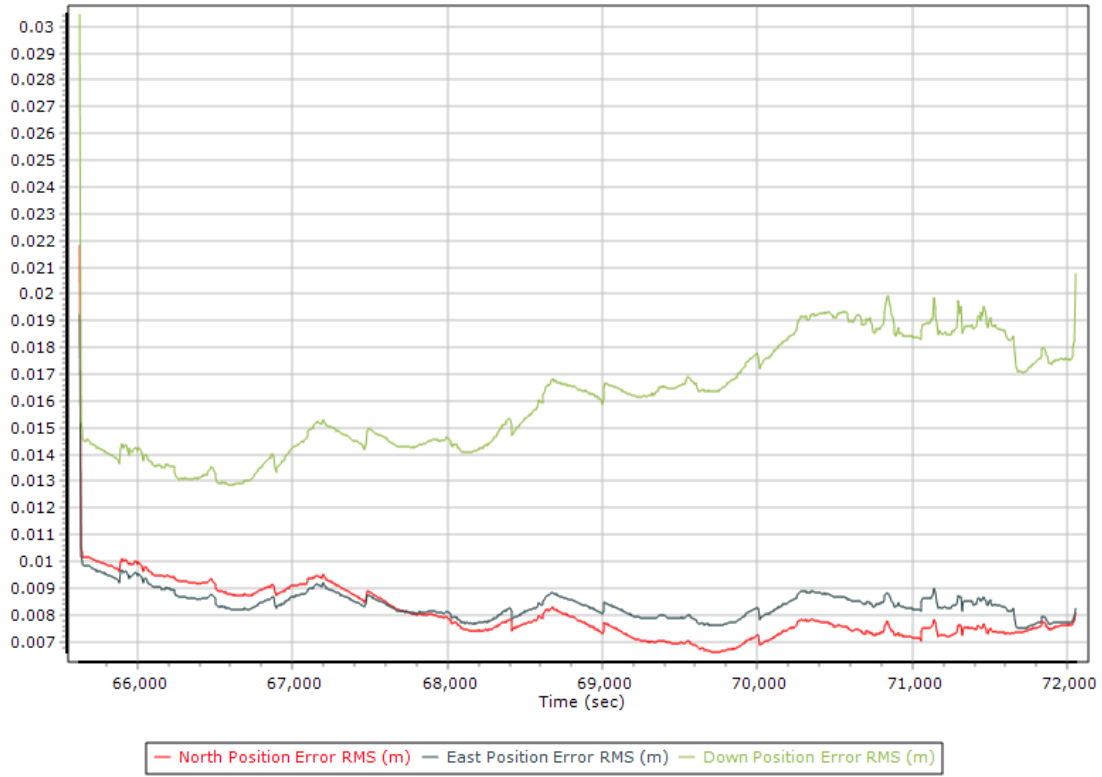


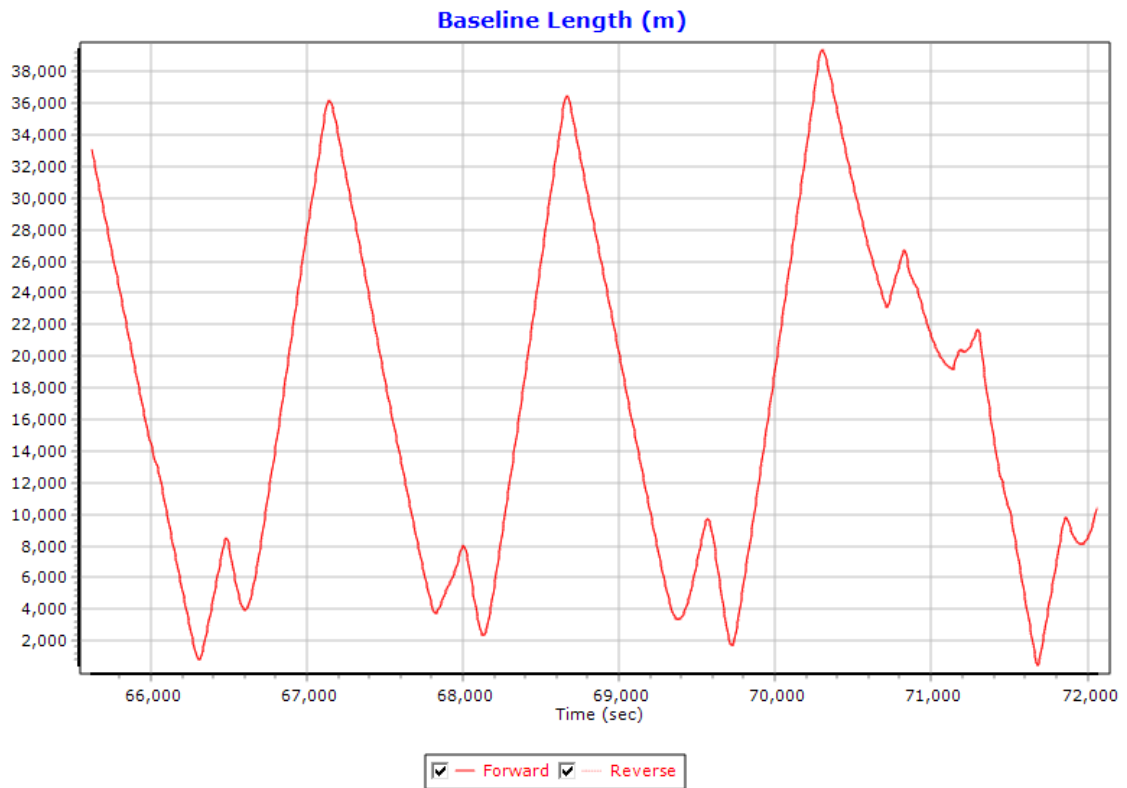
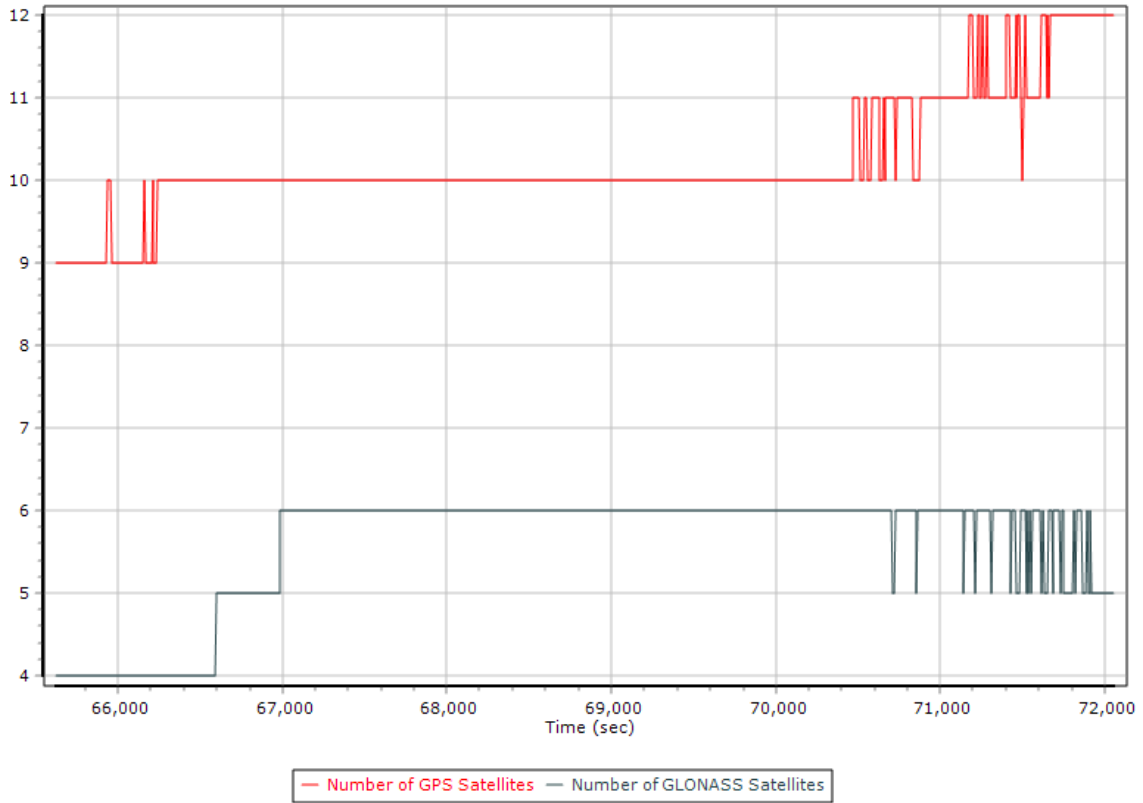
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000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

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

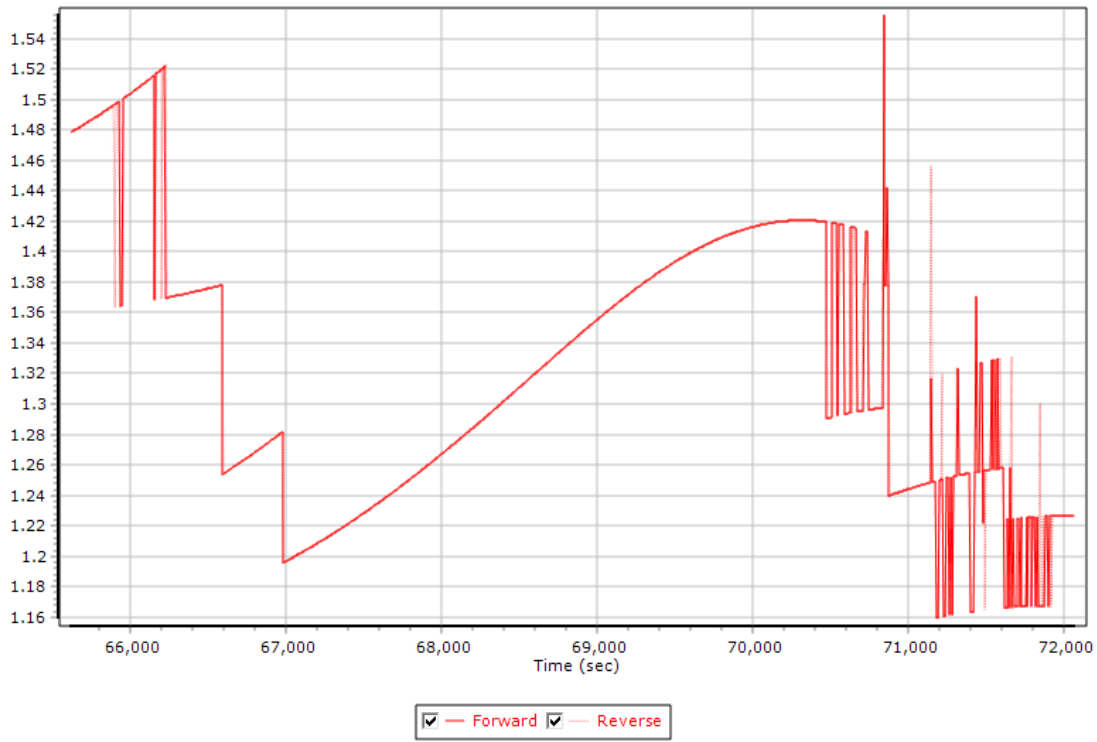
Timing									
Start	<input type="text" value="65621.330"/>								
End	<input type="text" value="72062.839"/>								
<input type="checkbox"/> Entire time interval									
<input checked="" type="checkbox"/> Seconds of start week									
UTC Offset	<input type="text" value="18.000"/>								
<table border="1"><thead><tr><th>Data</th><th>Incr. (sec)</th></tr></thead><tbody><tr><td>Output Record</td><td>0.005000</td></tr><tr><td>IMU</td><td>0.005000</td></tr><tr><td>Primary GNSS</td><td>1.000000</td></tr></tbody></table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000	
Data	Incr. (sec)								
Output Record	0.005000								
IMU	0.005000								
Primary GNSS	1.000000								



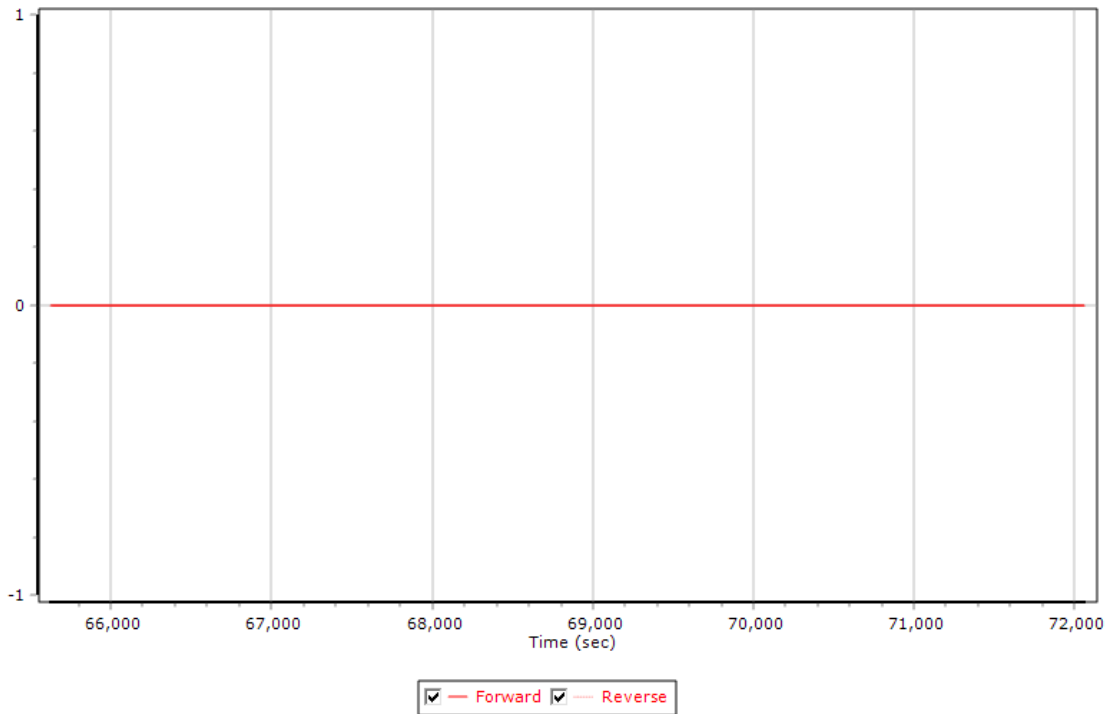




PDOP

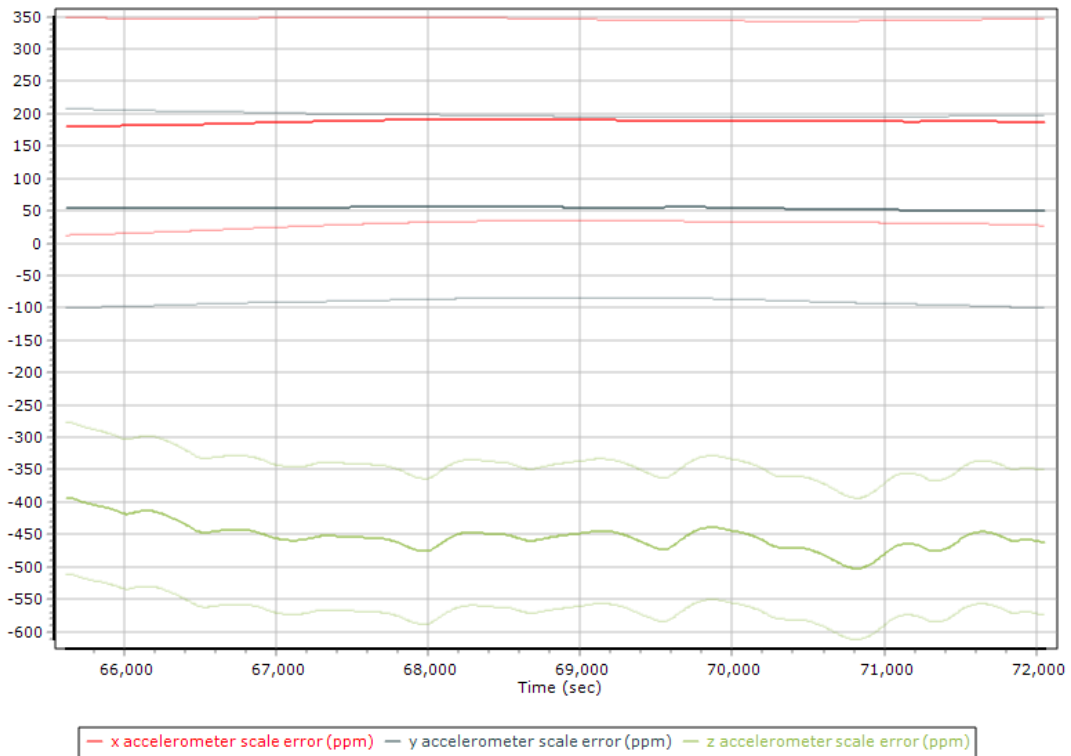
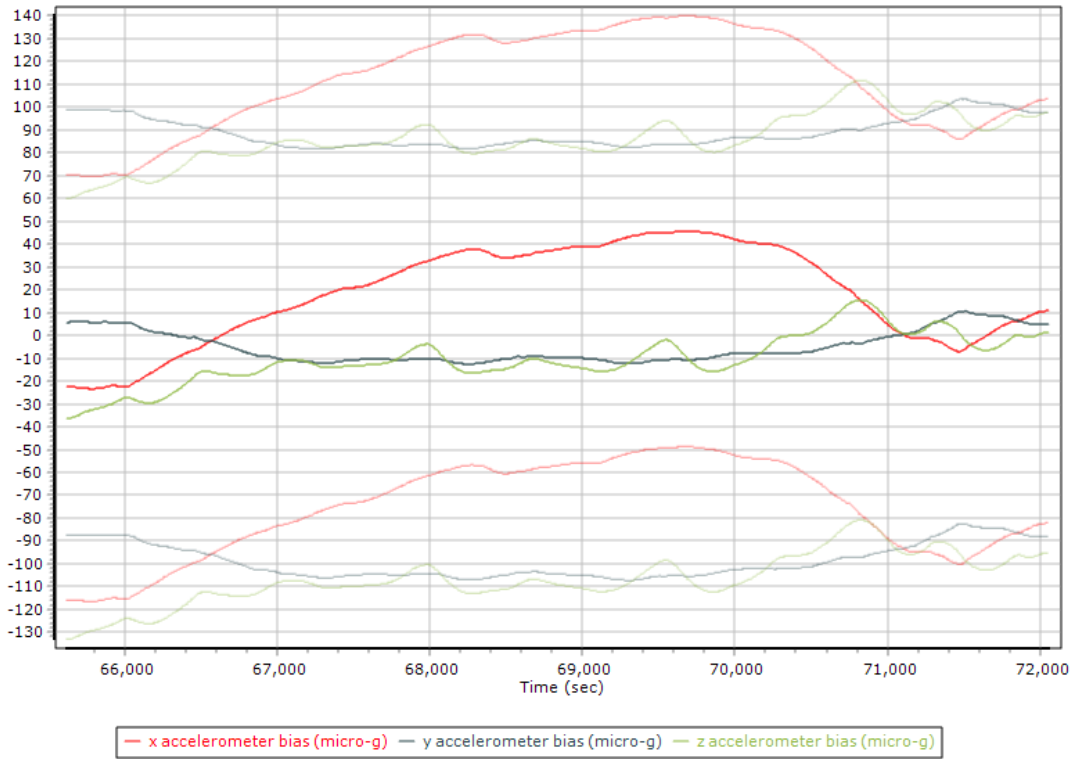


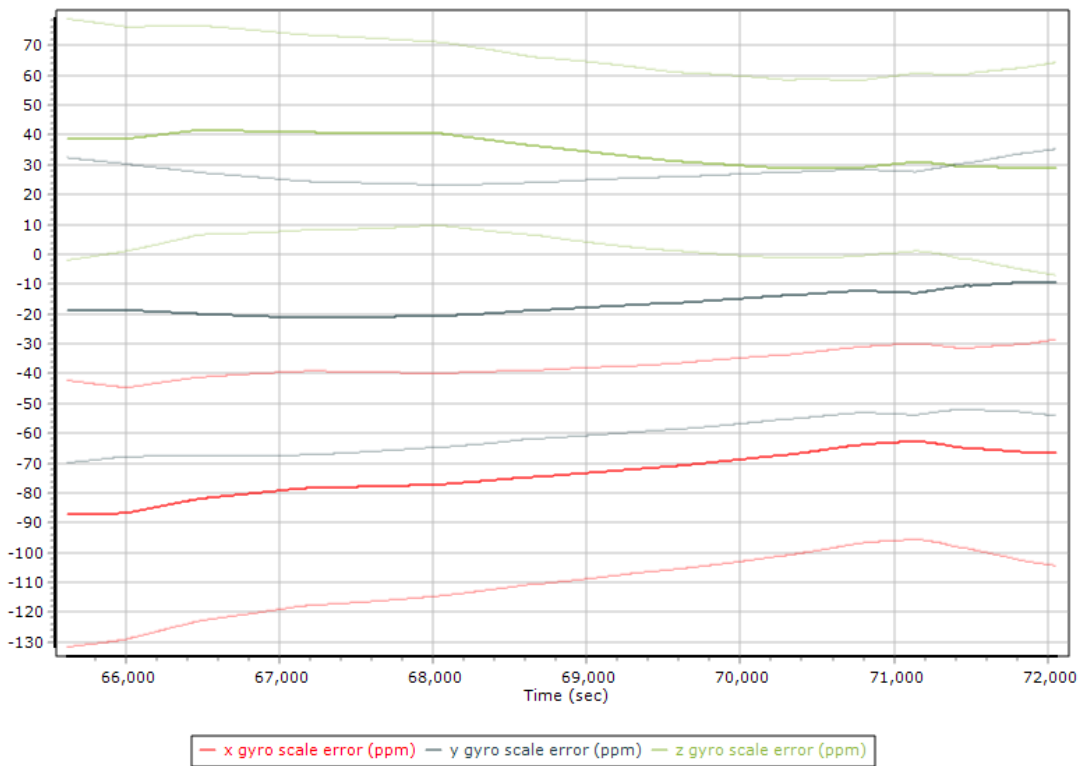
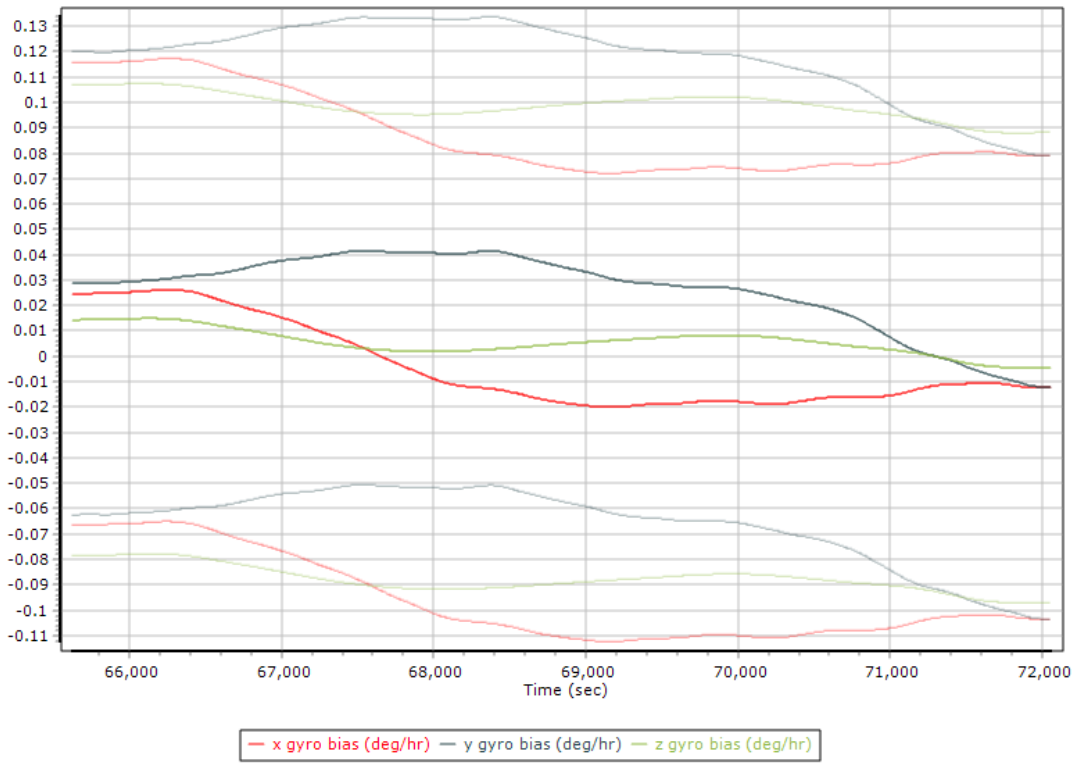
Processing mode



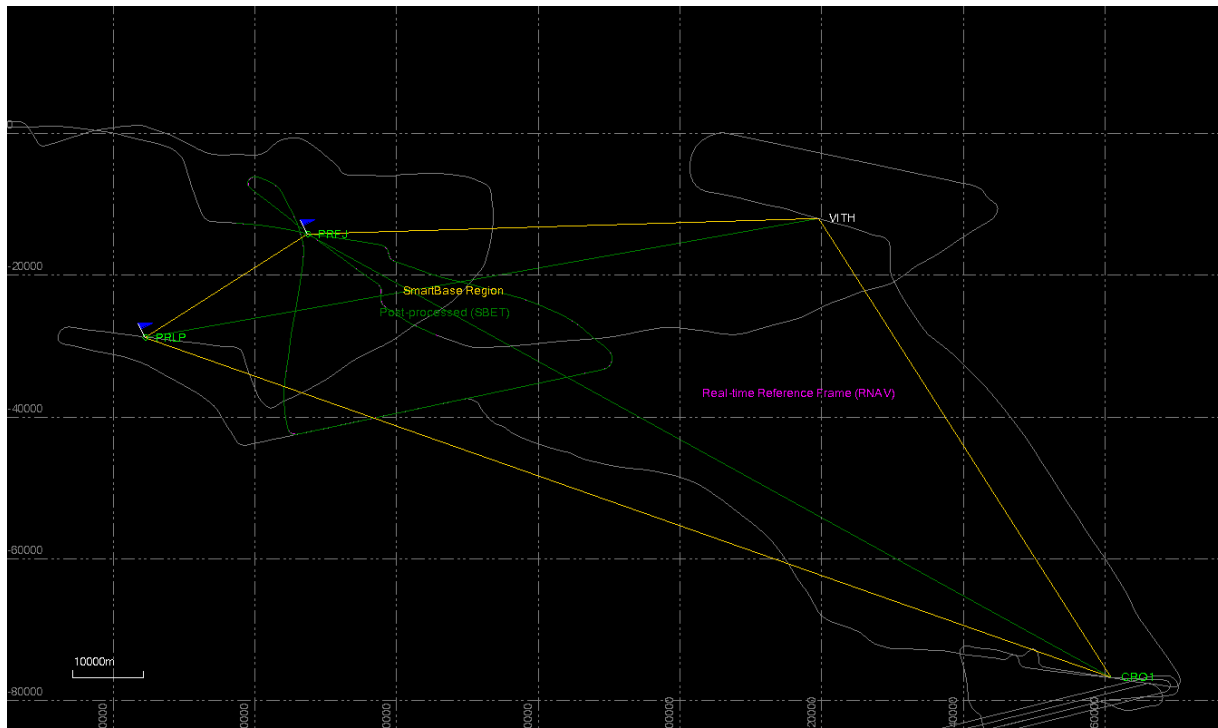
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





AZT18140B2



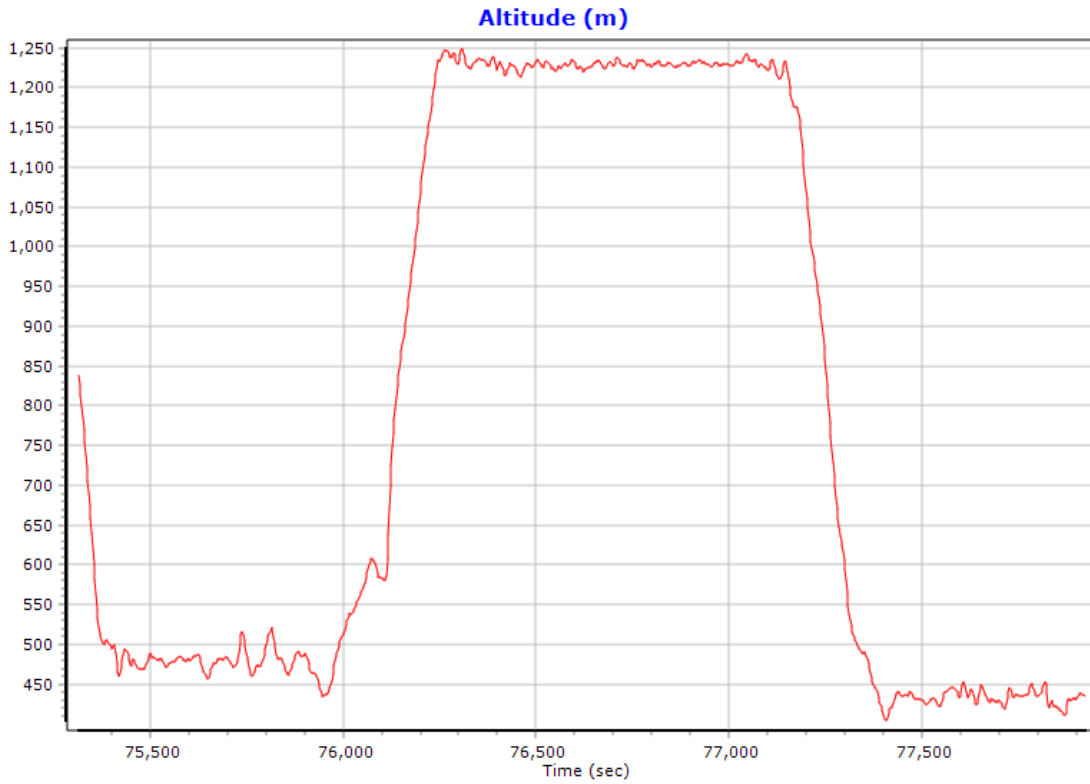
Stabilized Mount to IMU Lever Arm	Stabilized Mount to IMU Mounting Angles
X: -0.034 m	X: 0.000 deg
Y: -0.010 m	Y: 0.000 deg
Z: -0.352 m	Z: 0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	Aircraft to Stabilized Mount Mounting Angles
X: -0.049 m	X: 0.000 deg
Y: 0.003 m	Y: 0.000 deg
Z: -1.230 m	Z: 0.000 deg
Standard Deviation: <3cm 10cm 50cm 1m 10m	

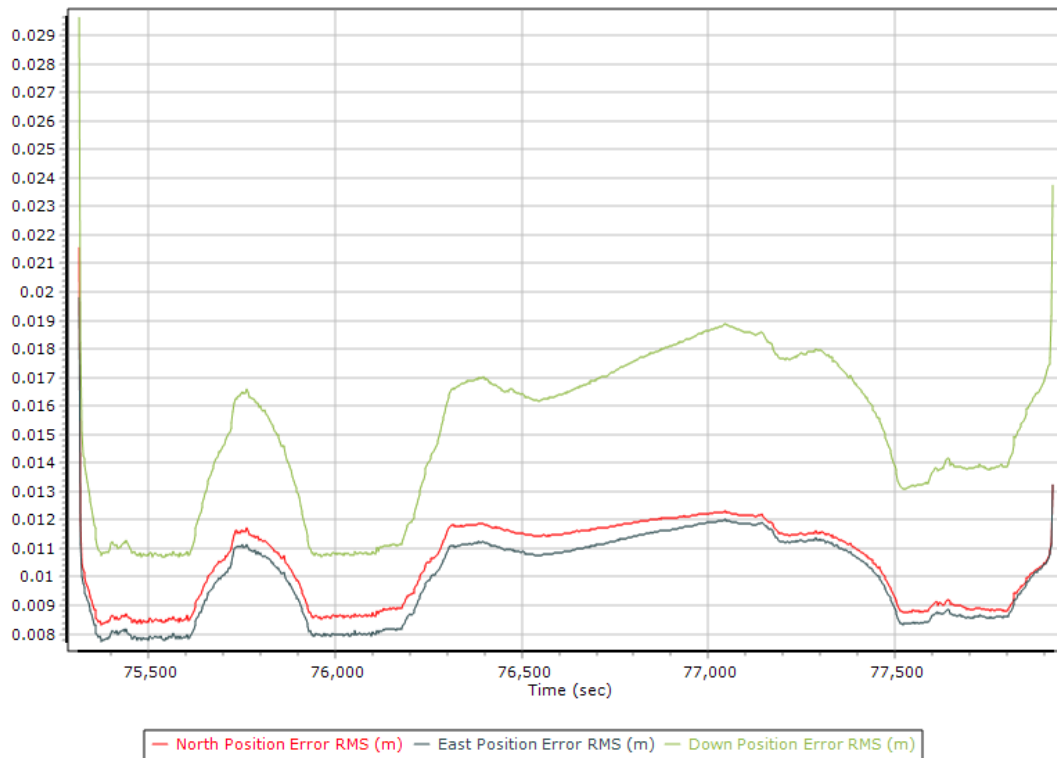
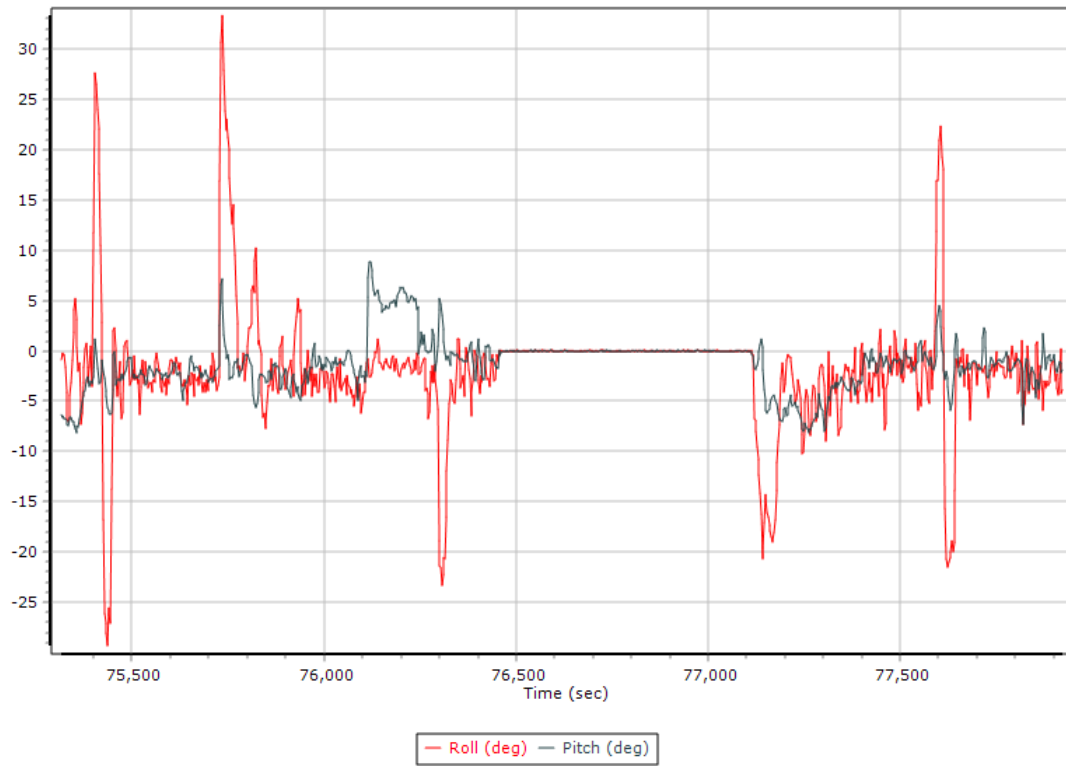
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

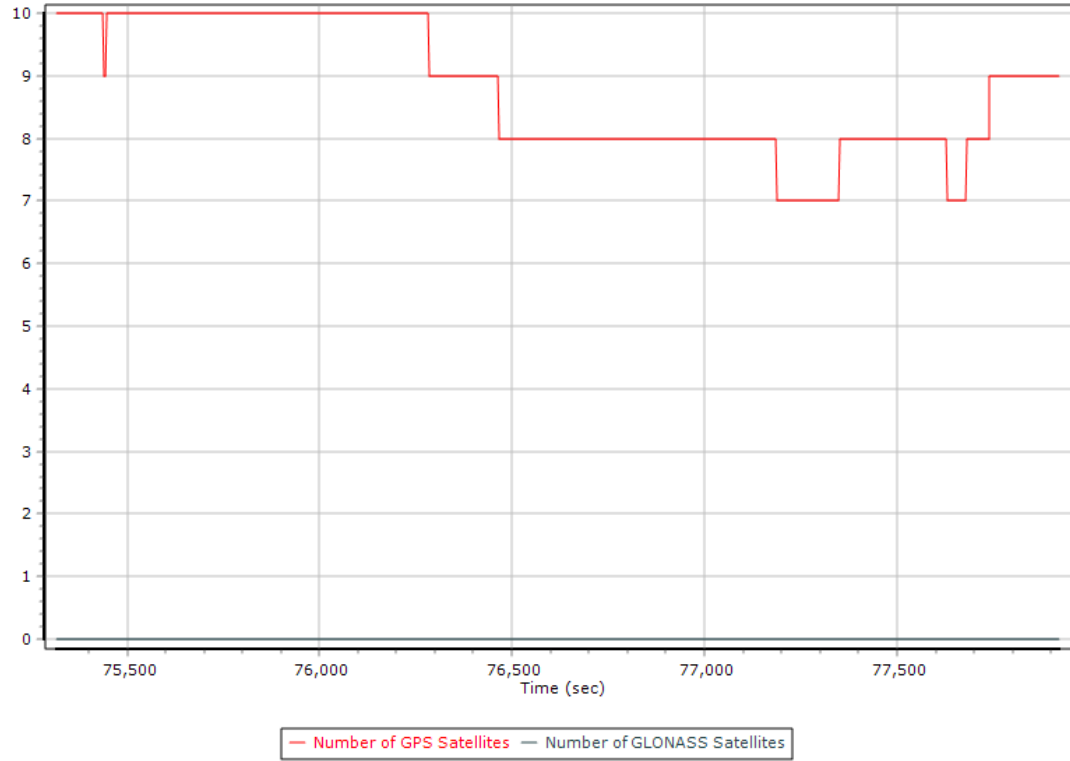
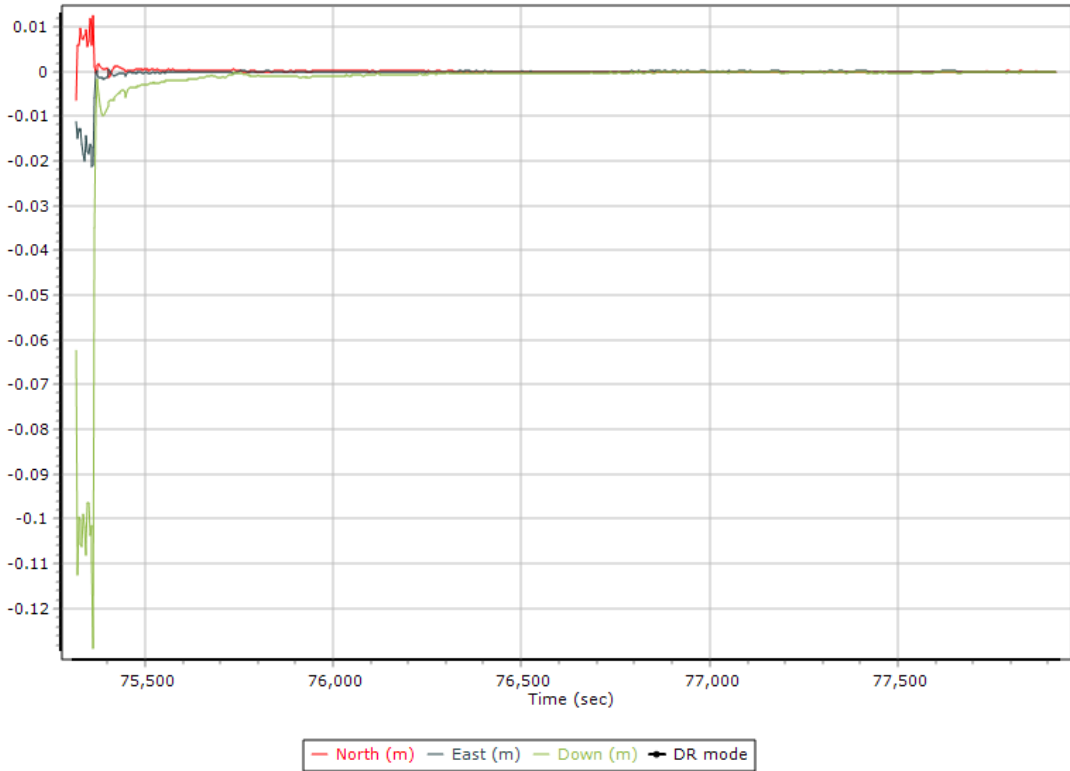
Timing

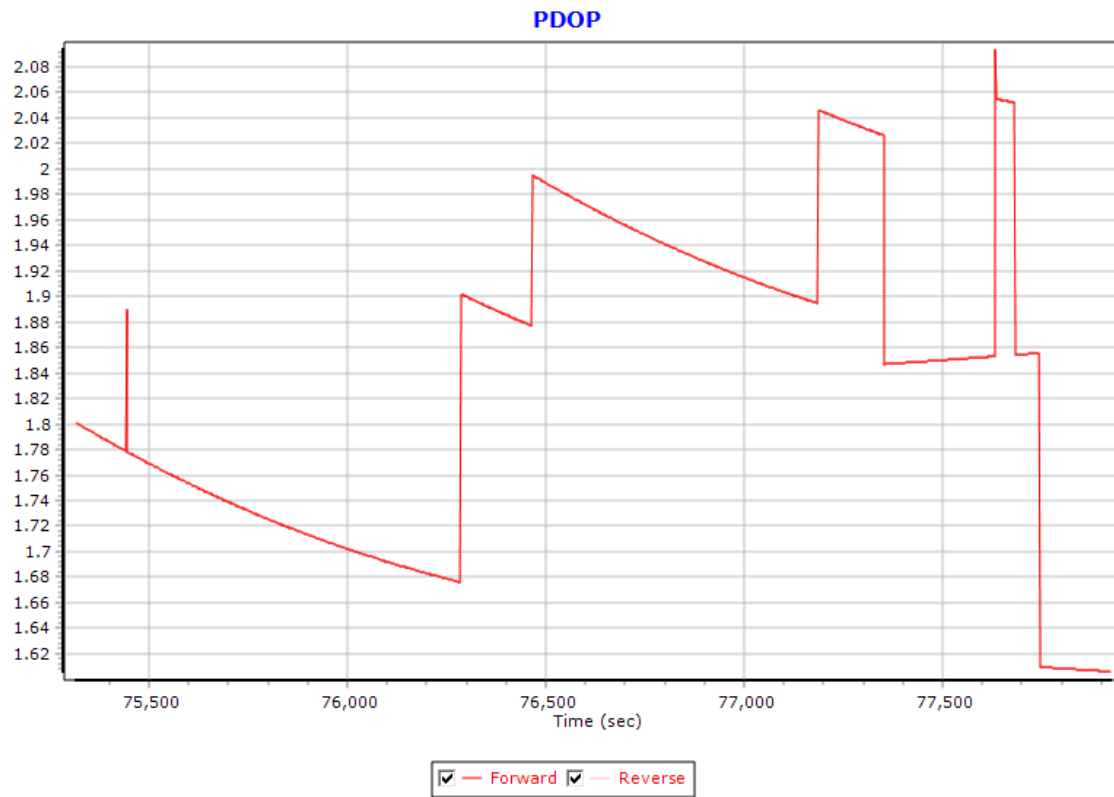
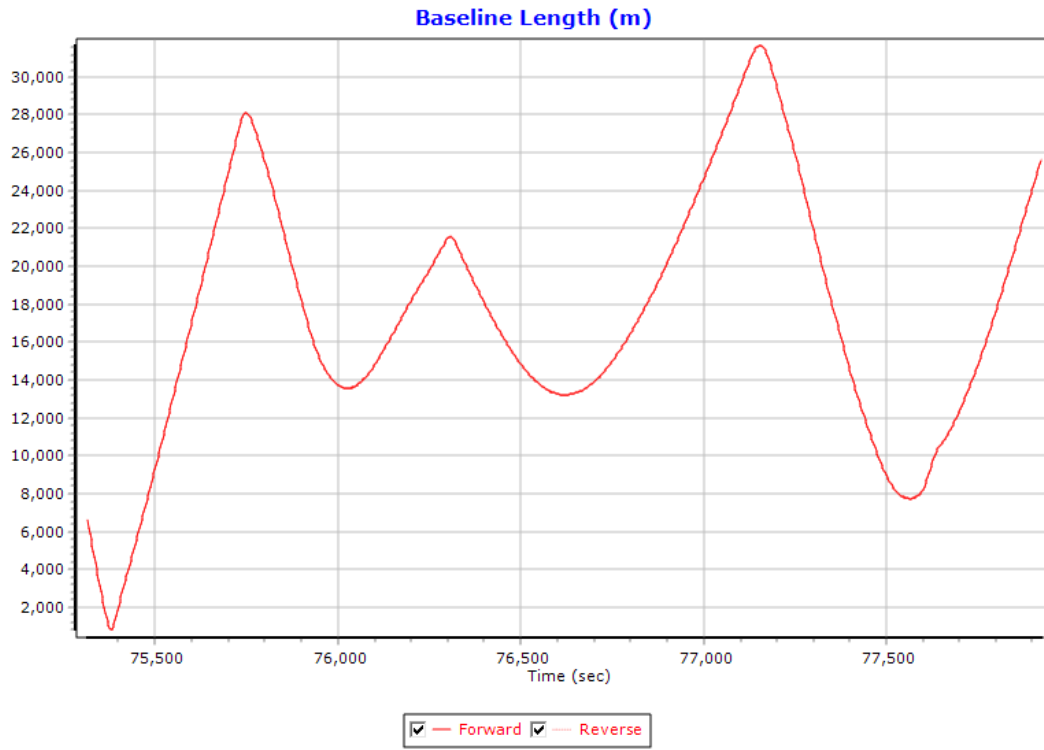
Start	<input type="text" value="75313.599"/>	Data	Incr. (sec)
End	<input type="text" value="77924.210"/>	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset

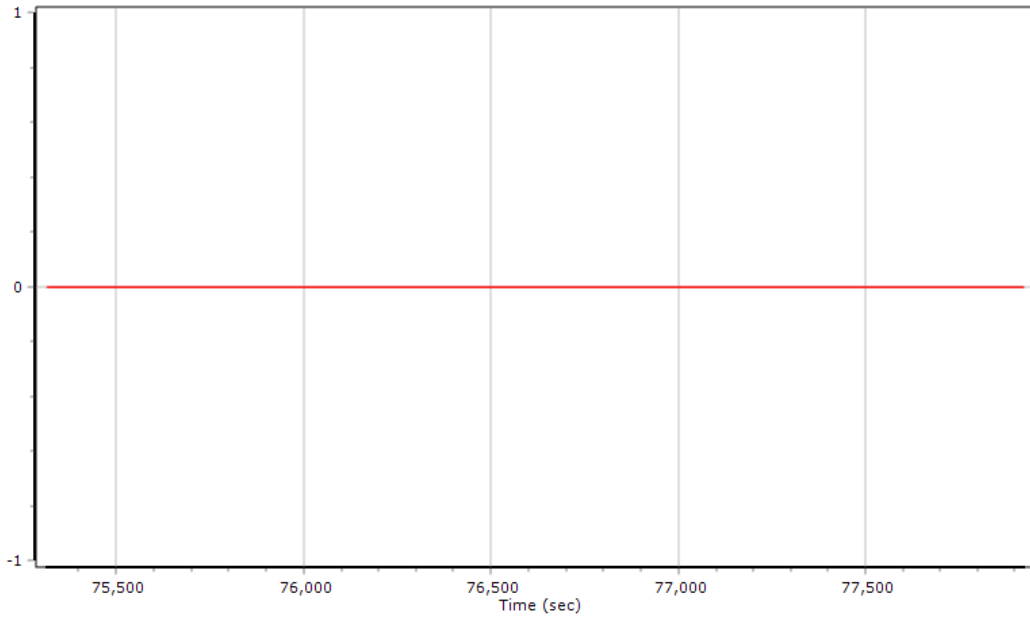








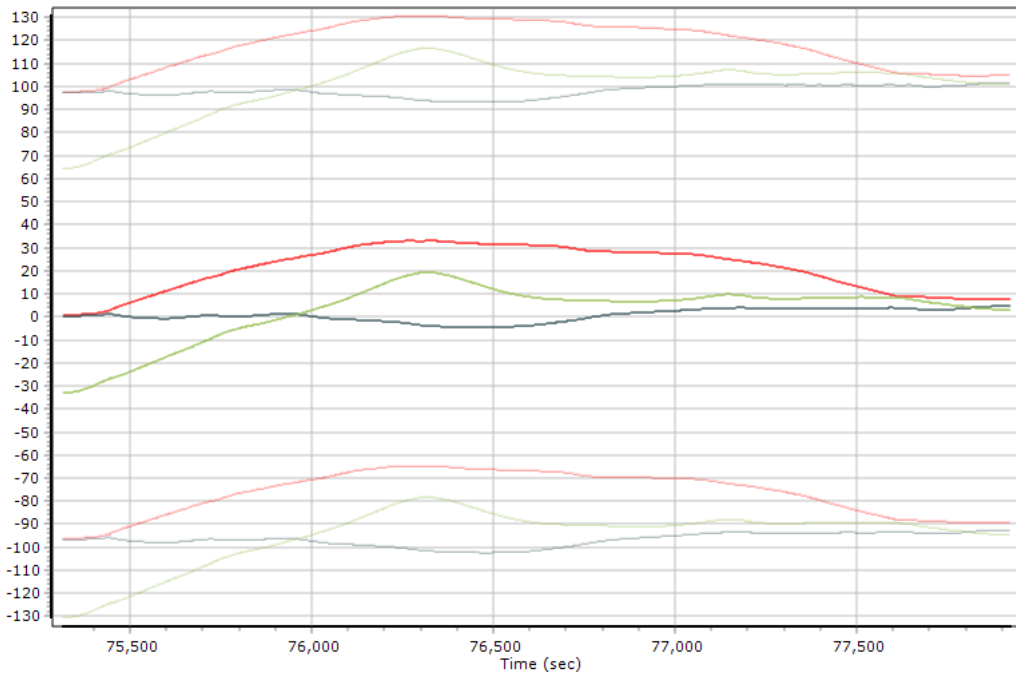
Processing mode



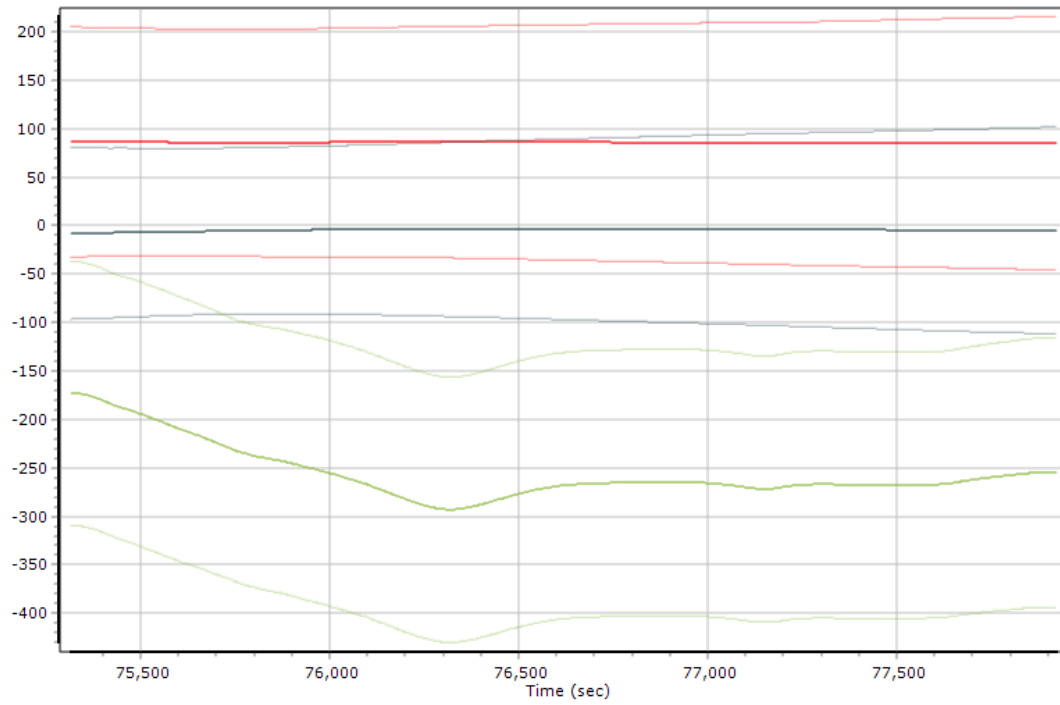
Forward Reverse

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

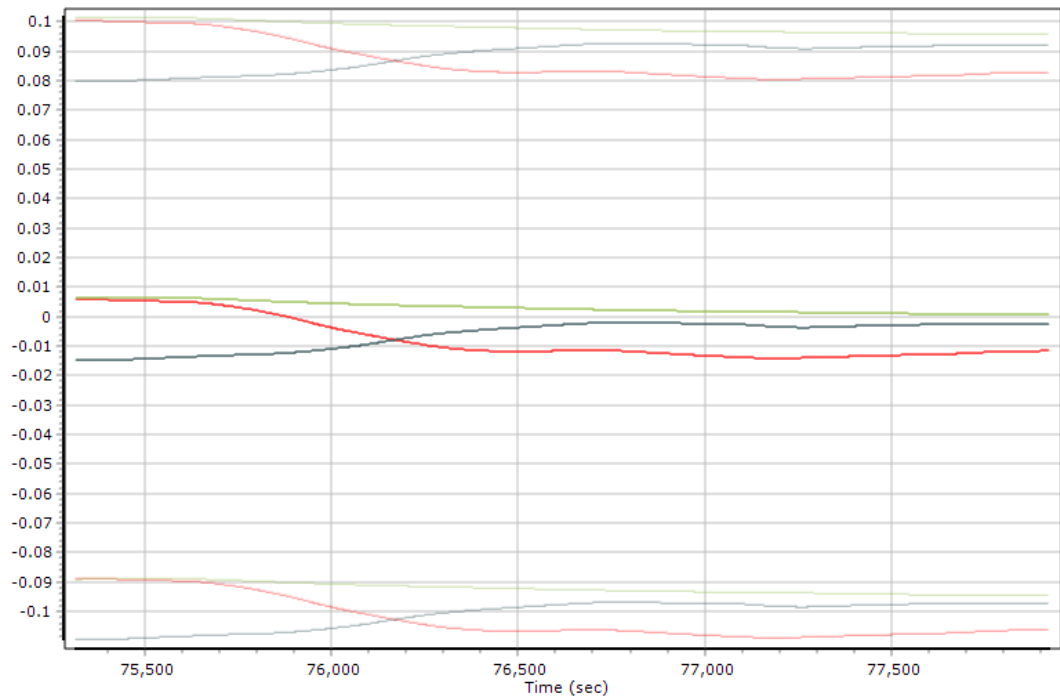
Sensor Errors



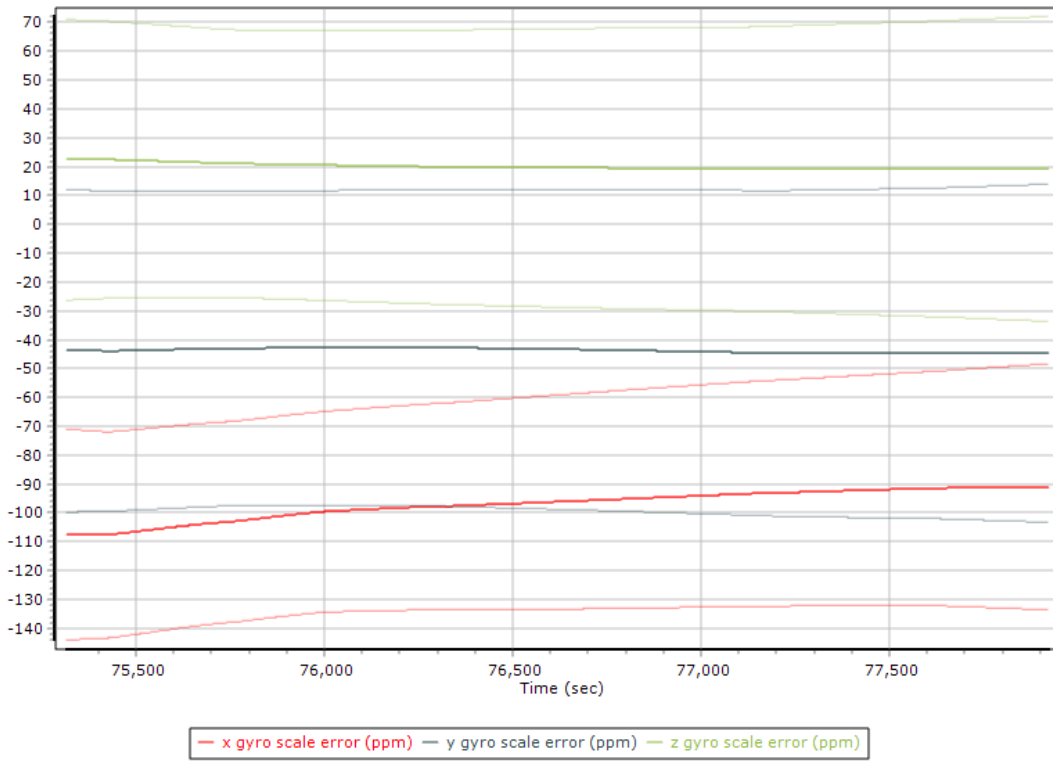
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



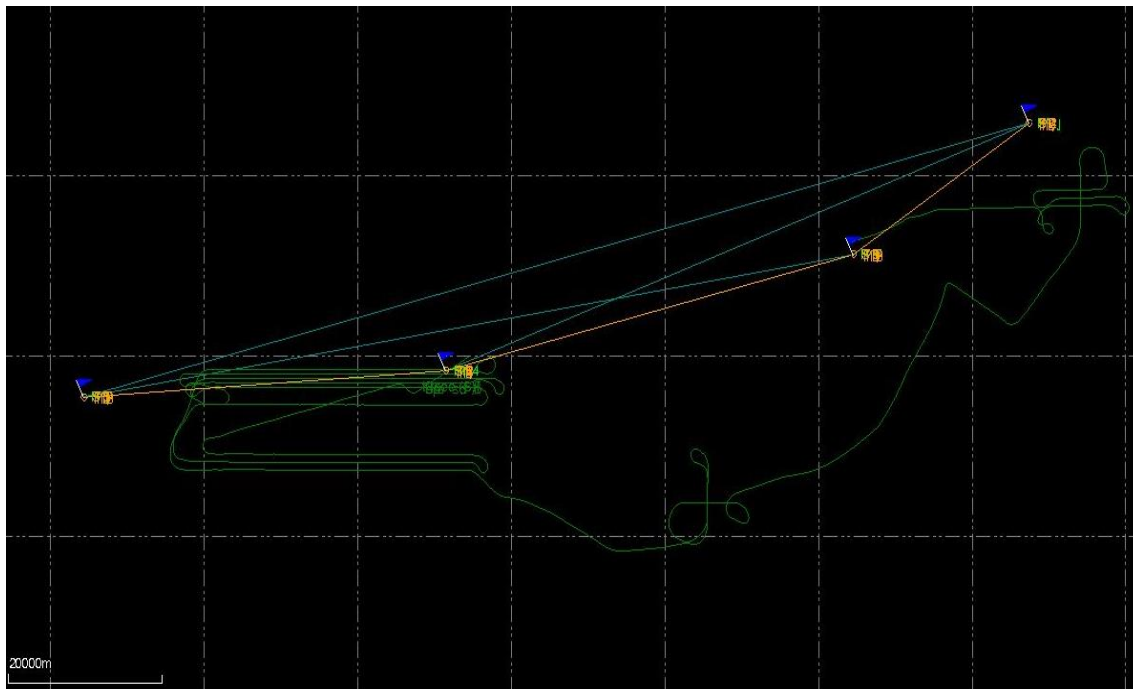
x accelerometer scale error (ppm) y accelerometer scale error (ppm) z accelerometer scale error (ppm)

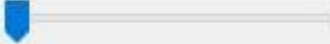


x gyro bias (deg/hr) y gyro bias (deg/hr) z gyro bias (deg/hr)



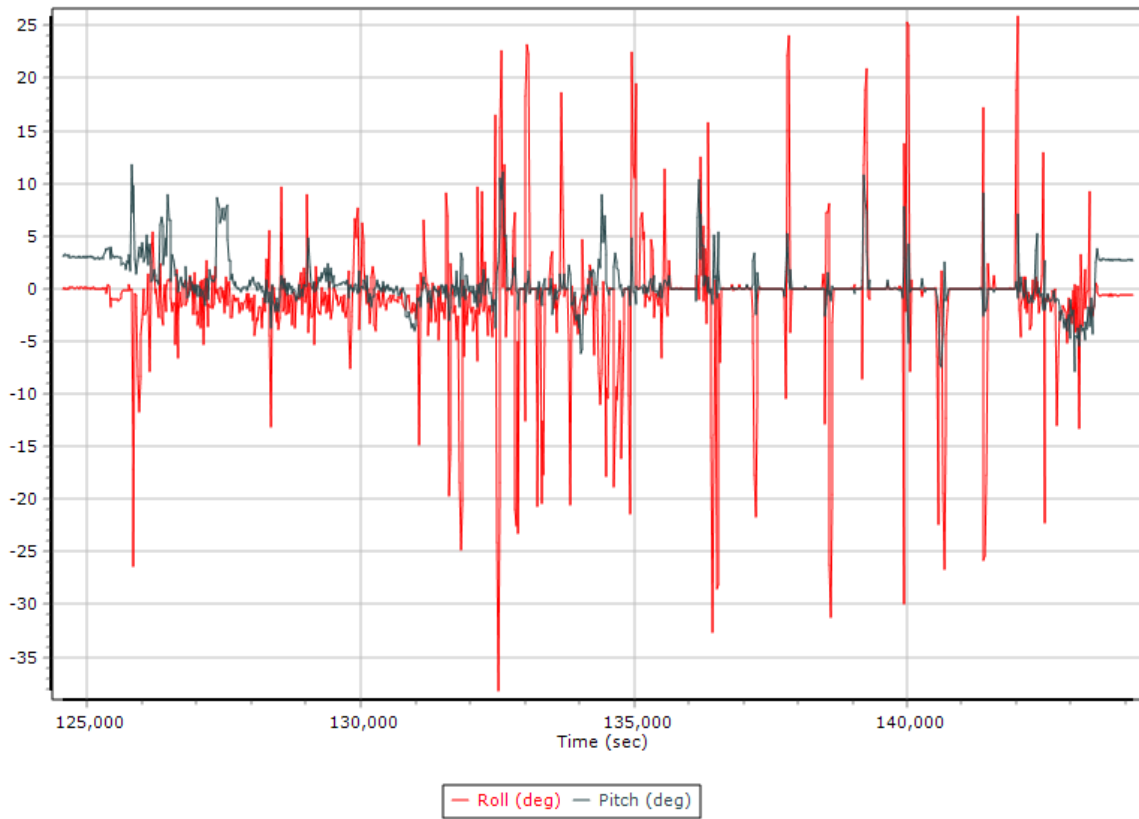
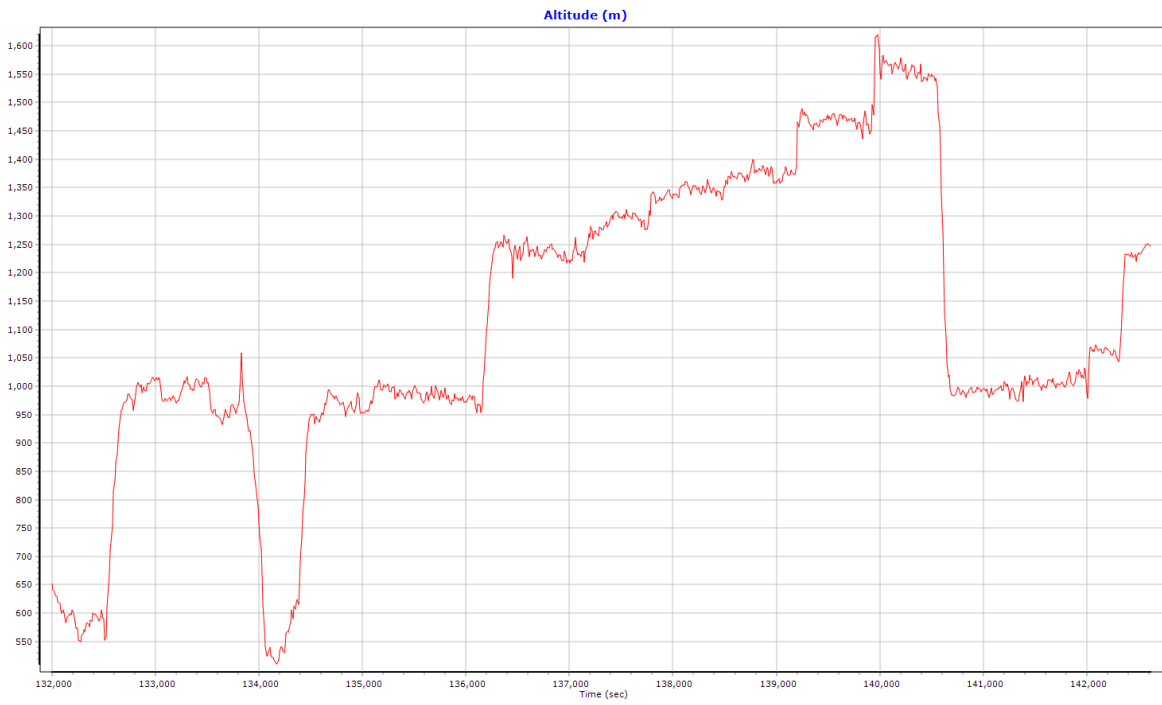
AZT18141A

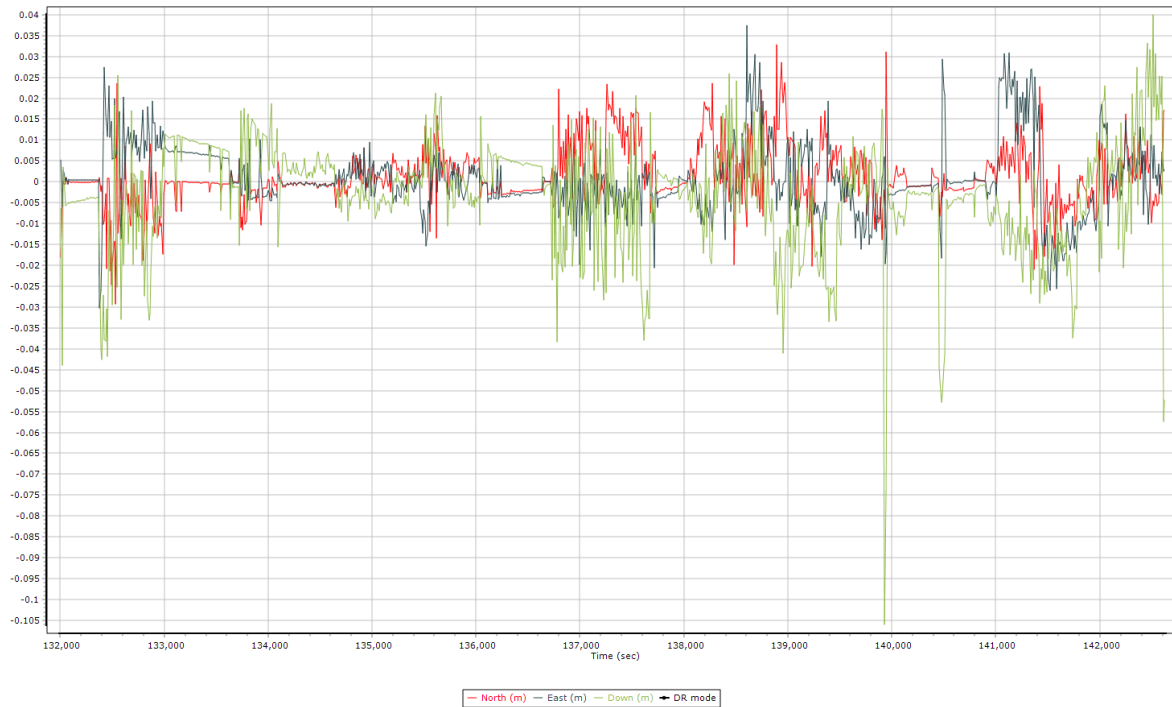
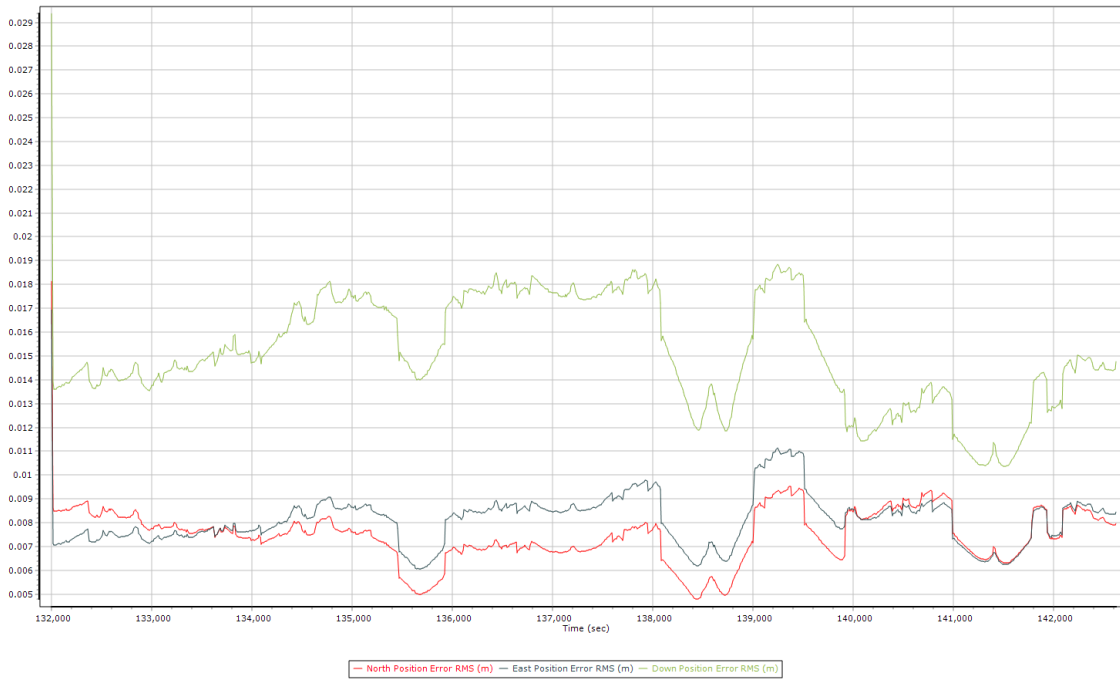


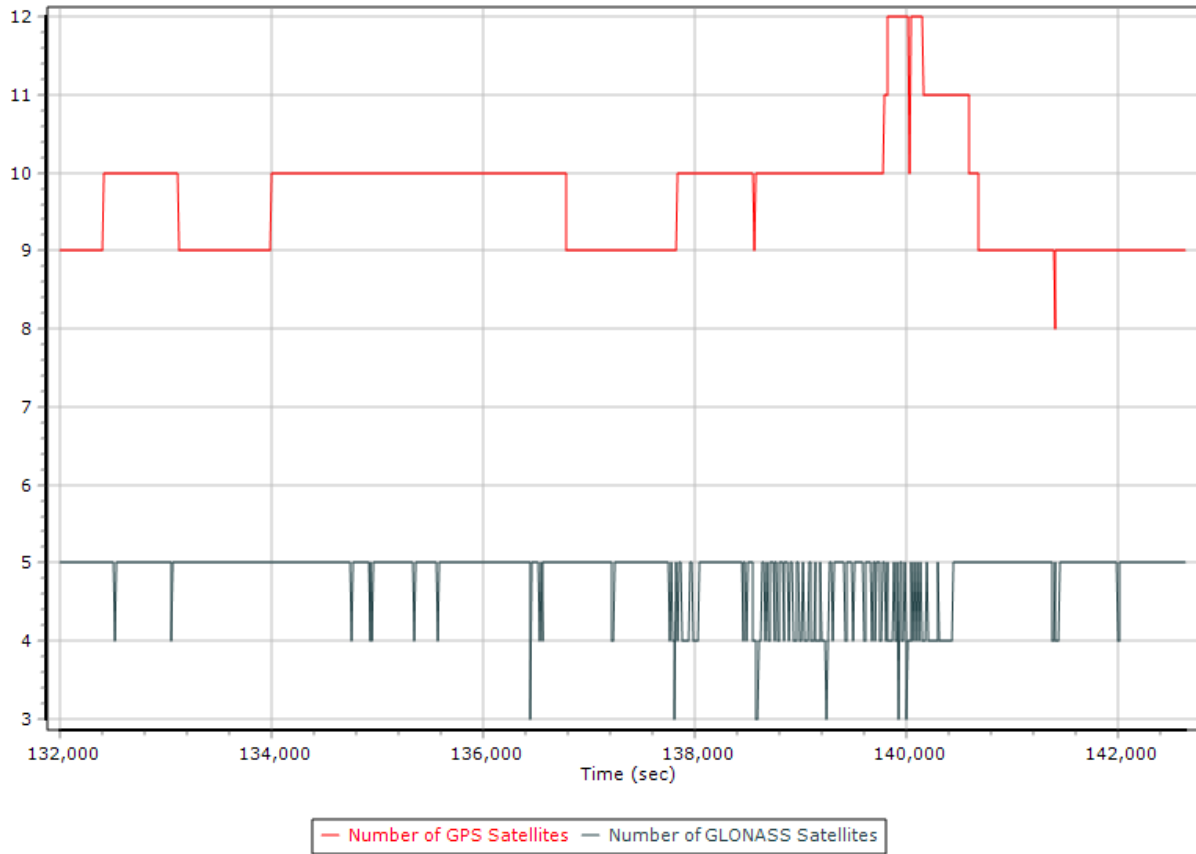
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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			
	<3cm 10cm 50cm 1m 10m		

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

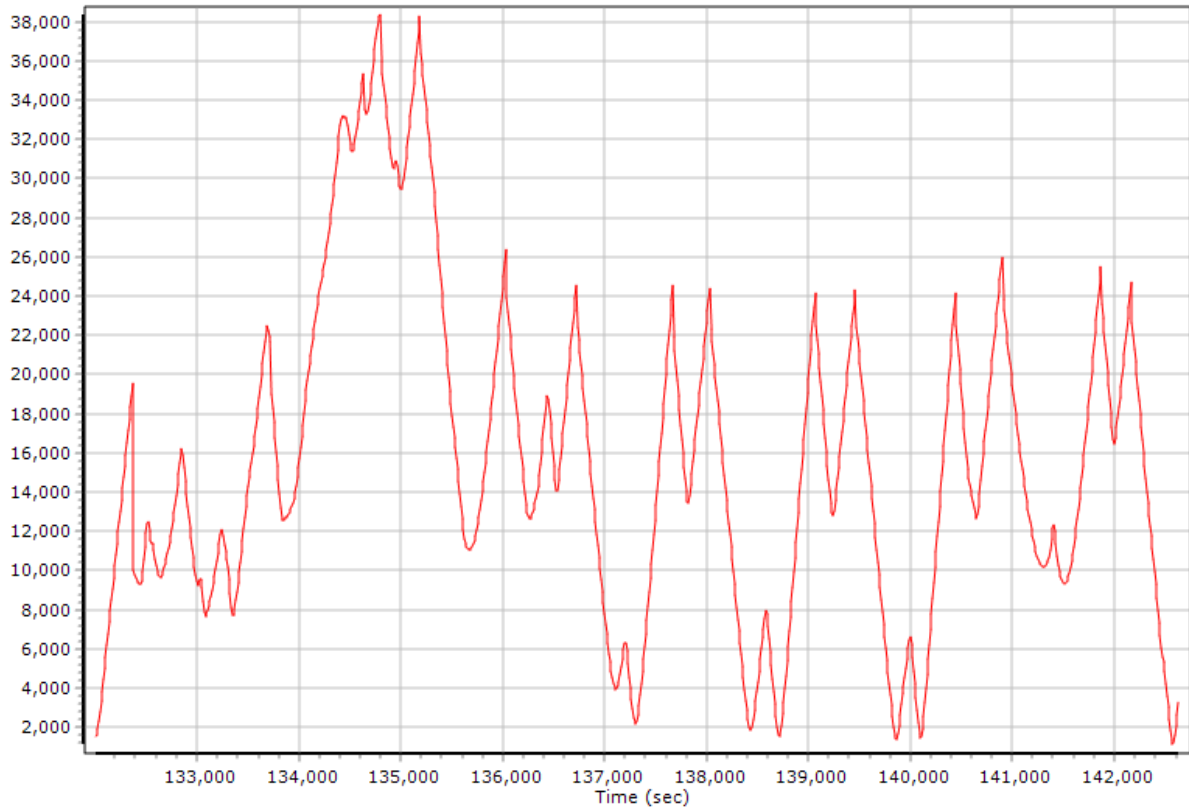
Timing									
Start	<input type="text" value="139900.000"/>								
End	<input type="text" value="142633.578"/>								
<input type="checkbox"/> Entire time interval									
<input checked="" type="checkbox"/> Seconds of start week									
UTC Offset	<input type="text" value="18.000"/>								
<table border="1"><thead><tr><th>Data</th><th>Incr. (sec)</th></tr></thead><tbody><tr><td>Output Record</td><td>0.005000</td></tr><tr><td>IMU</td><td>0.005000</td></tr><tr><td>Primary GNSS</td><td>1.000000</td></tr></tbody></table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000	
Data	Incr. (sec)								
Output Record	0.005000								
IMU	0.005000								
Primary GNSS	1.000000								



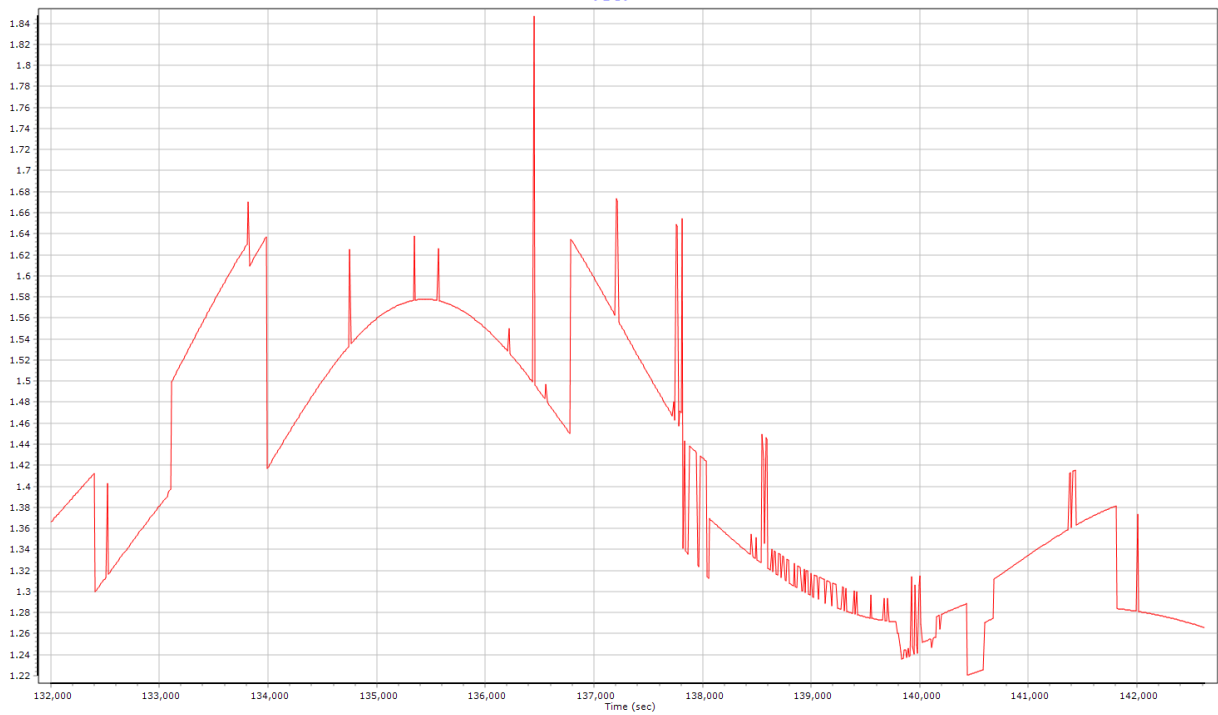


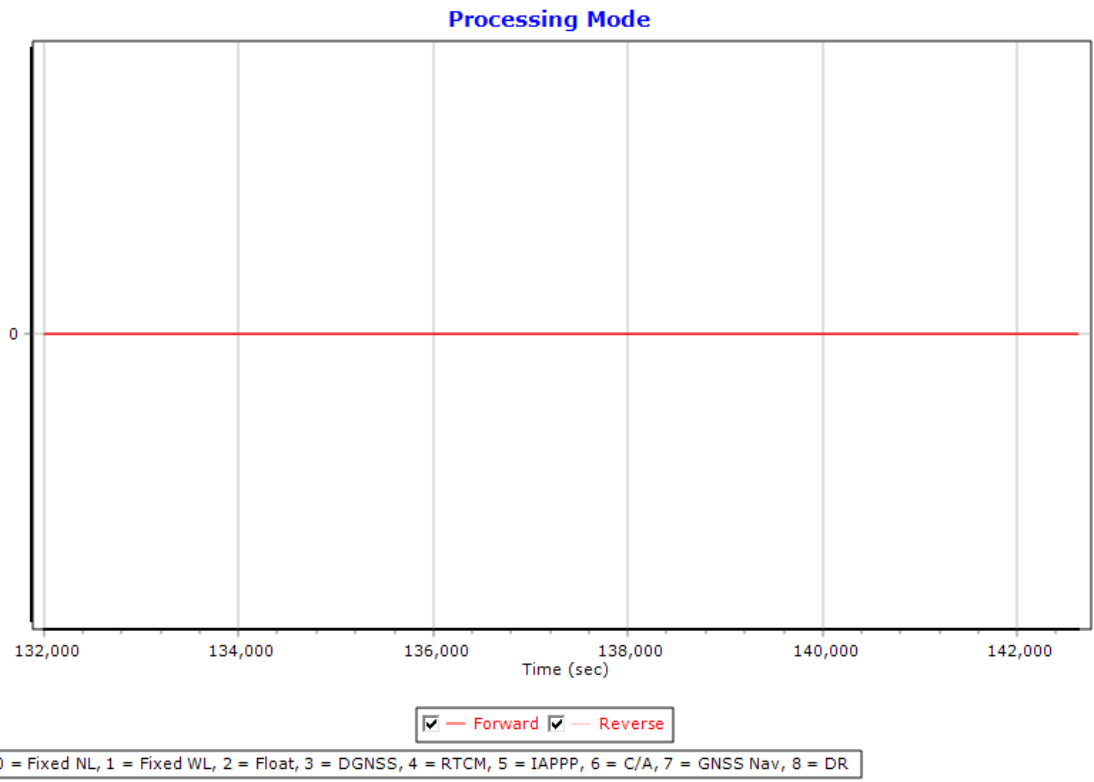


Baseline Length(m)

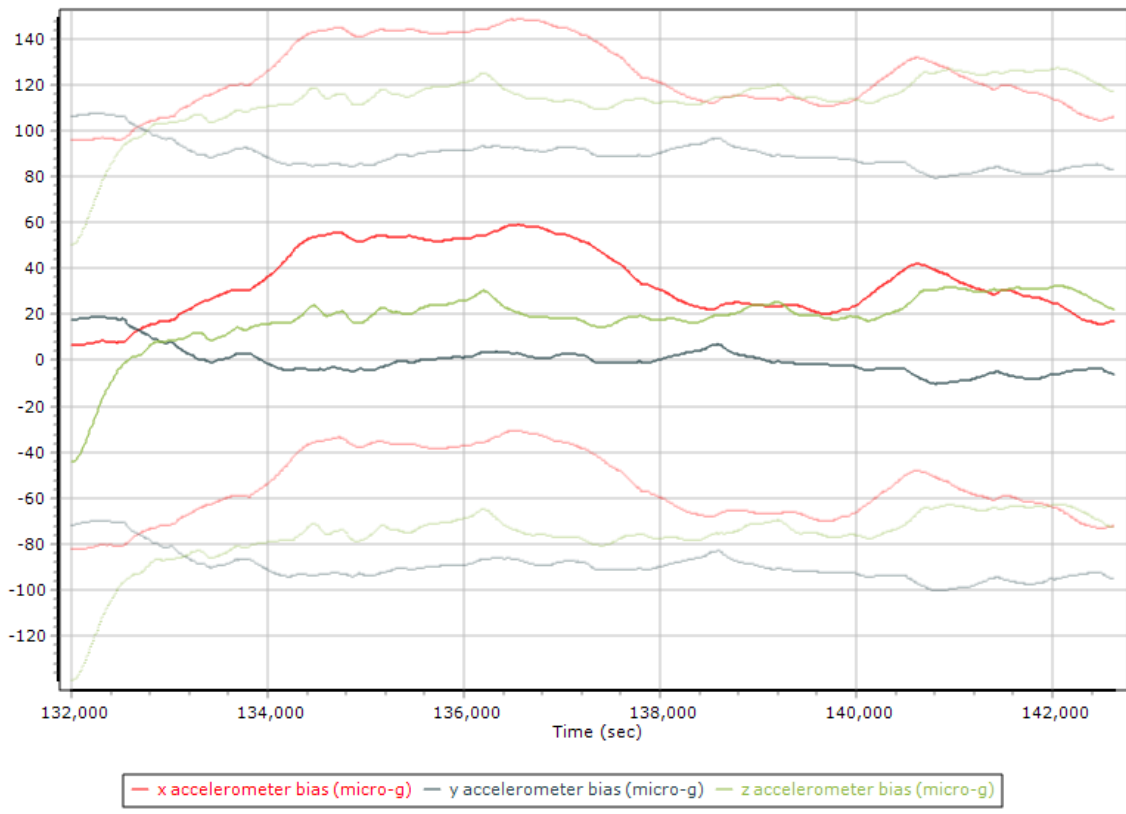


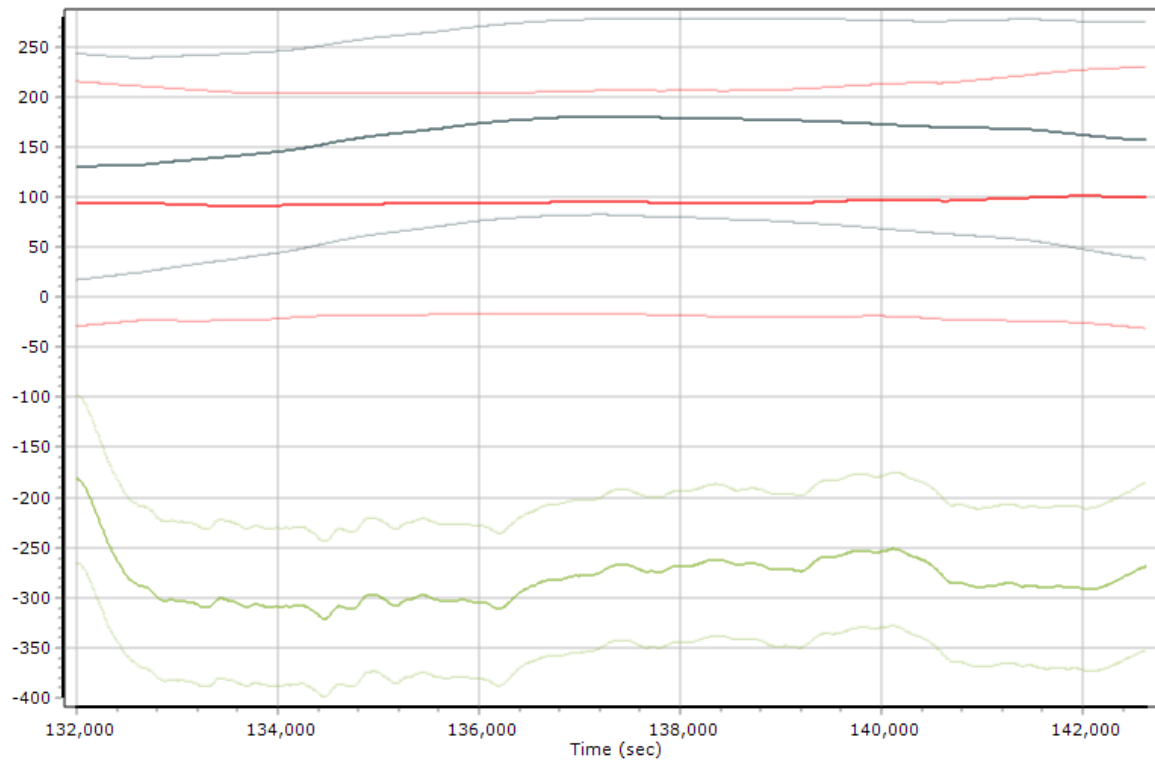
PDOP



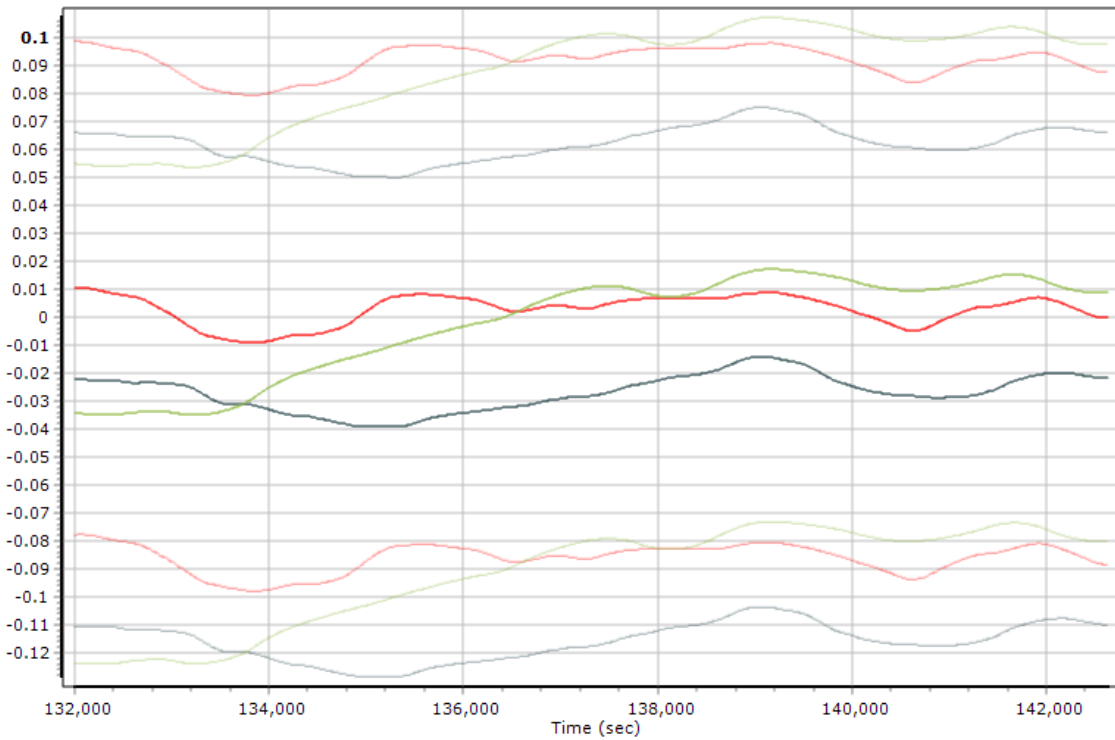


Sensor Errors

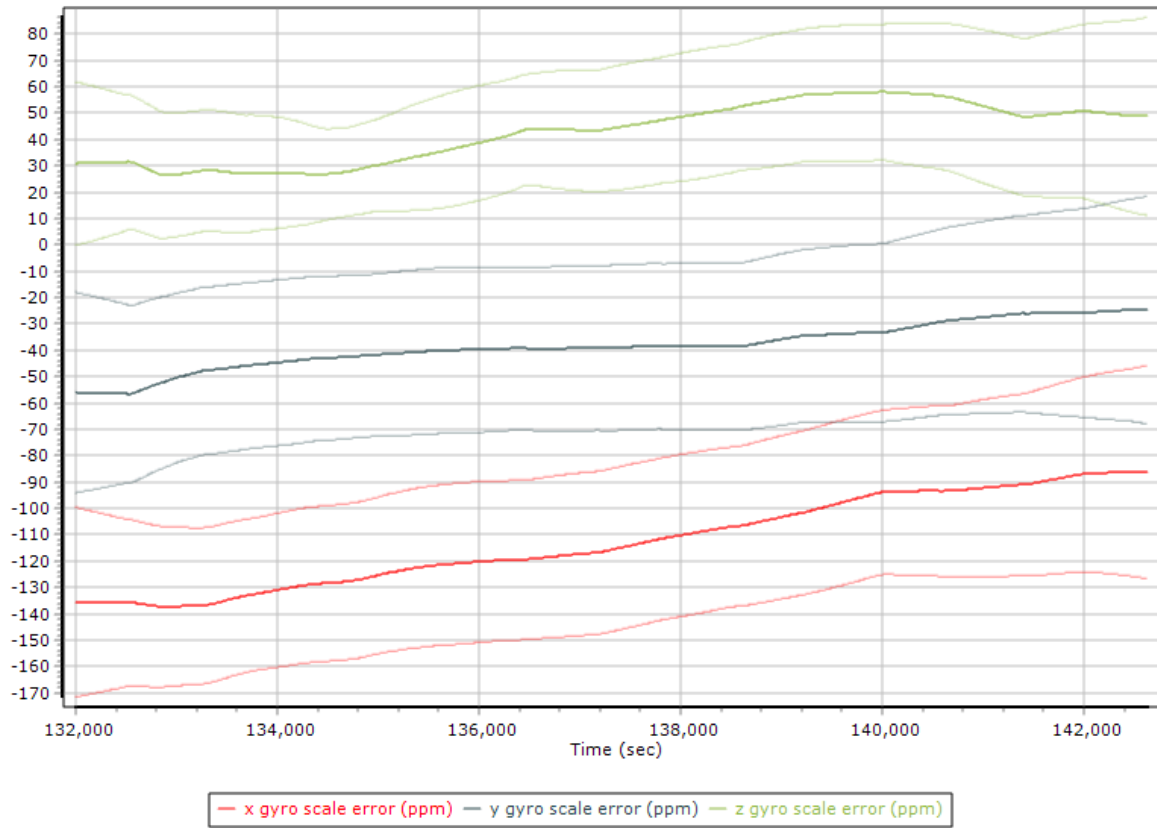




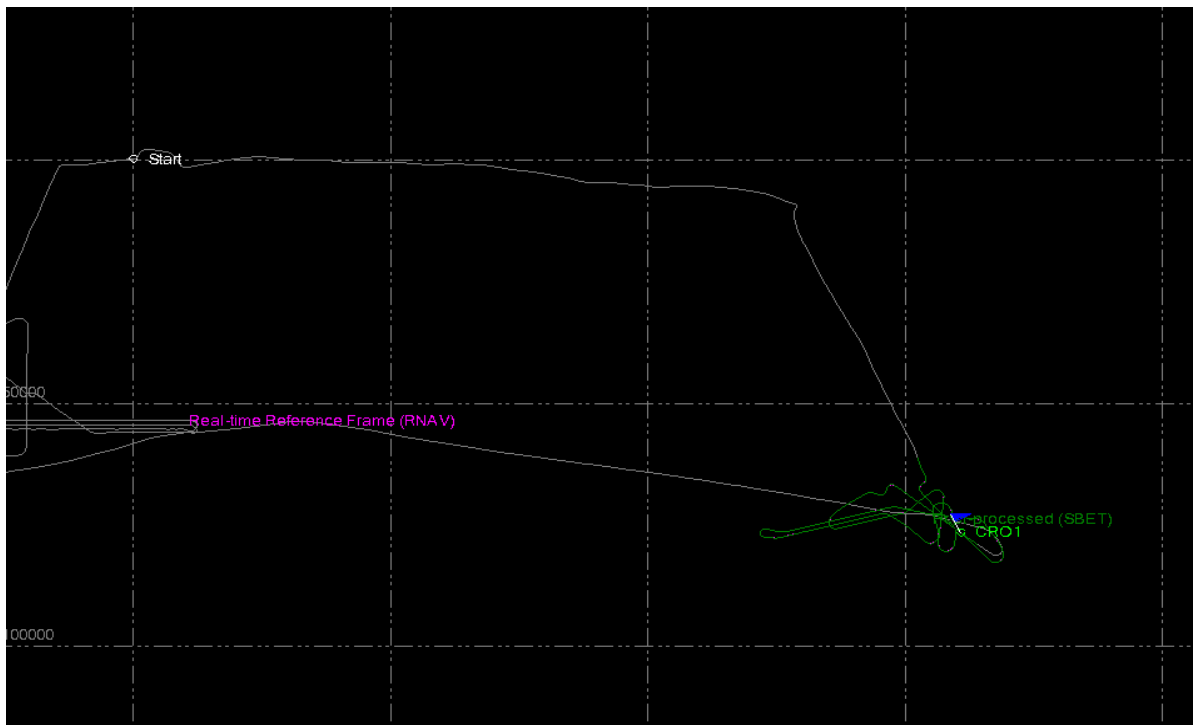
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



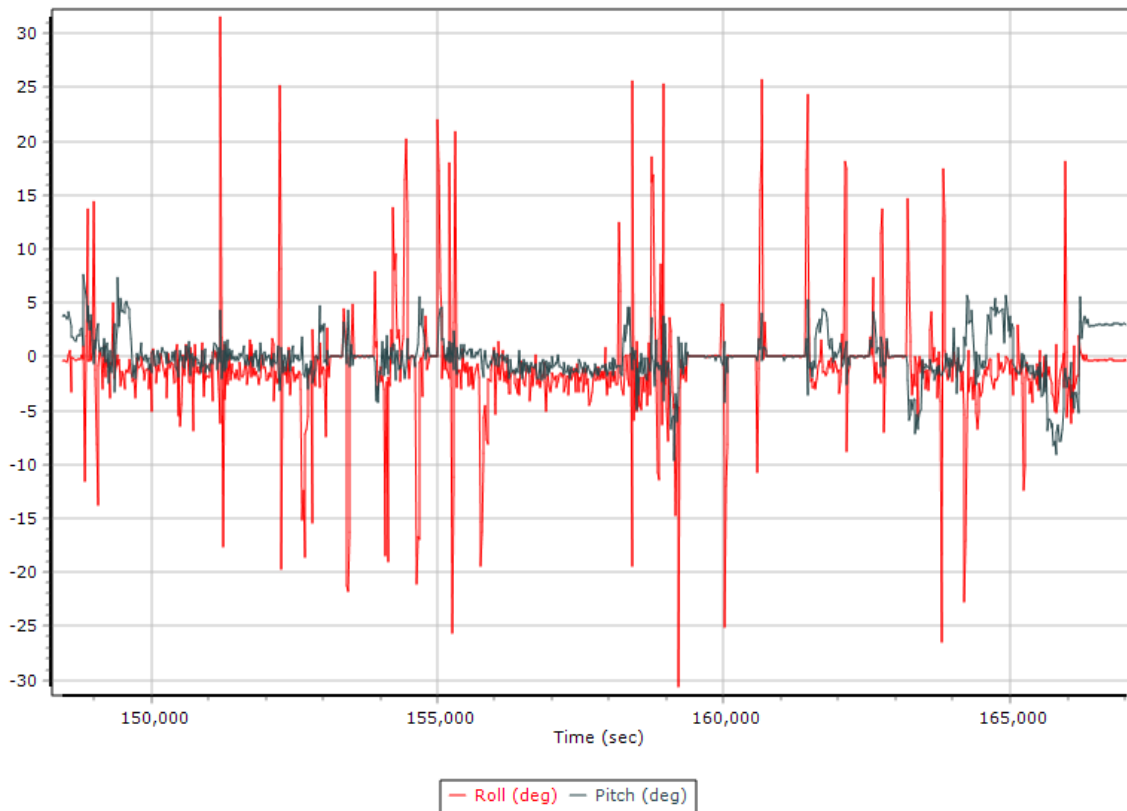
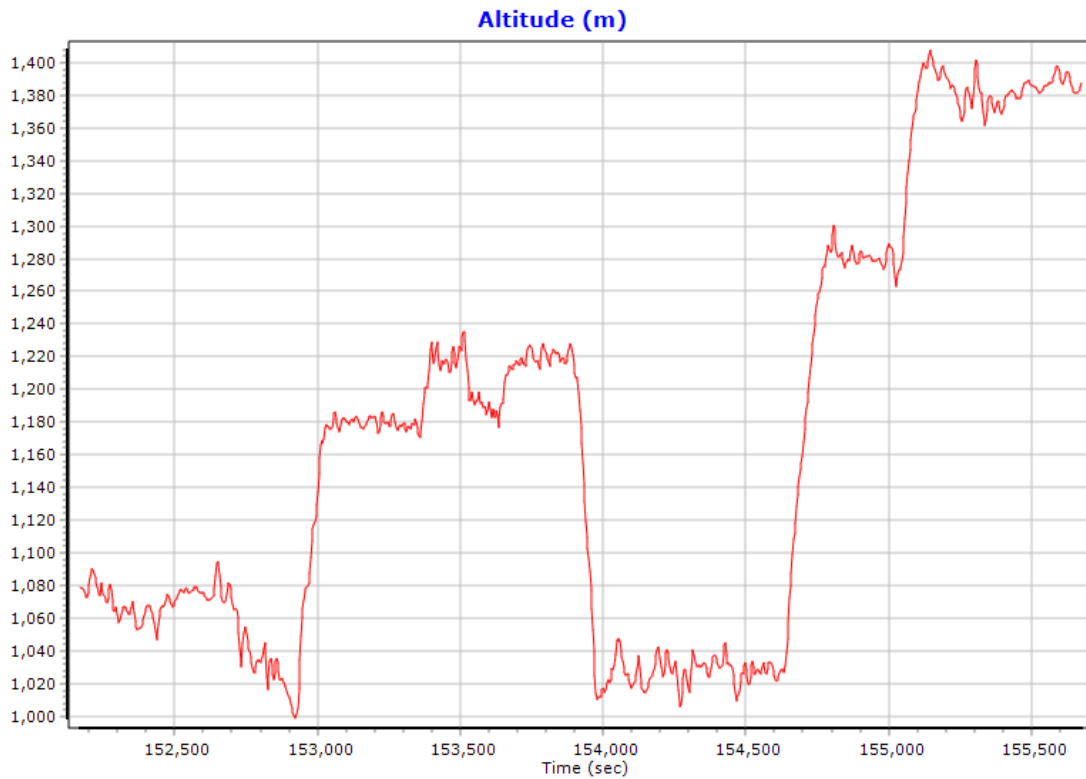
AZT18141B1

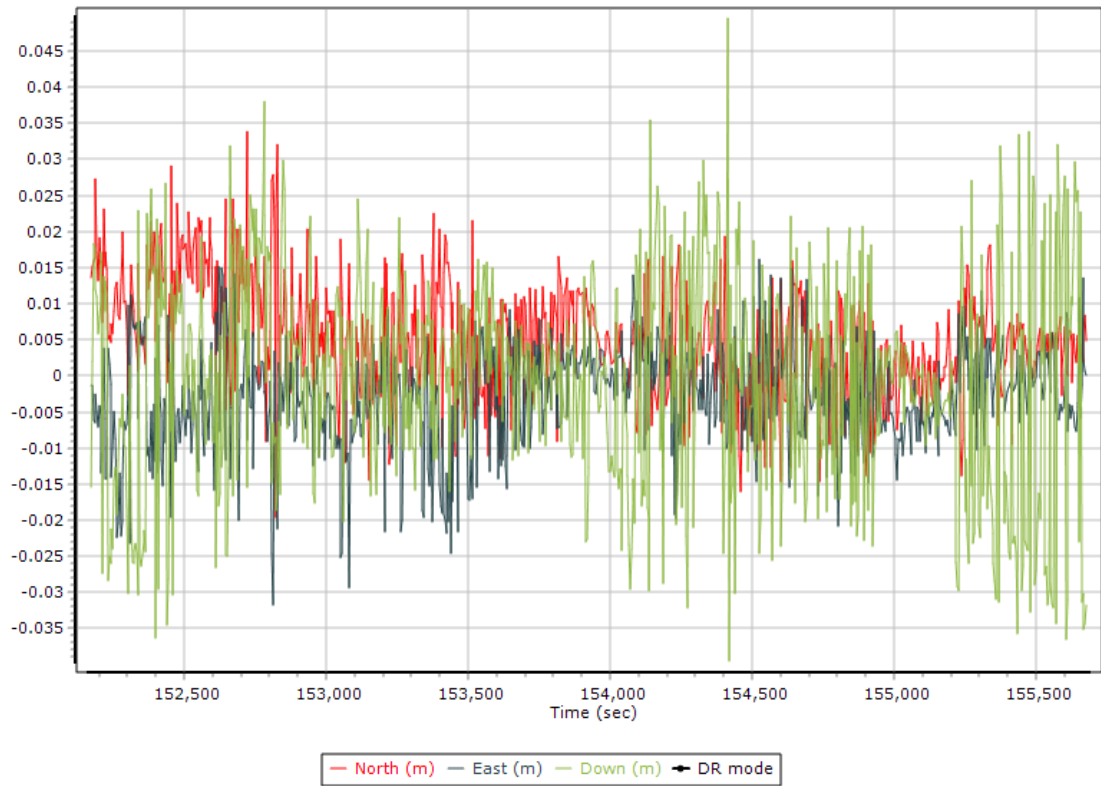
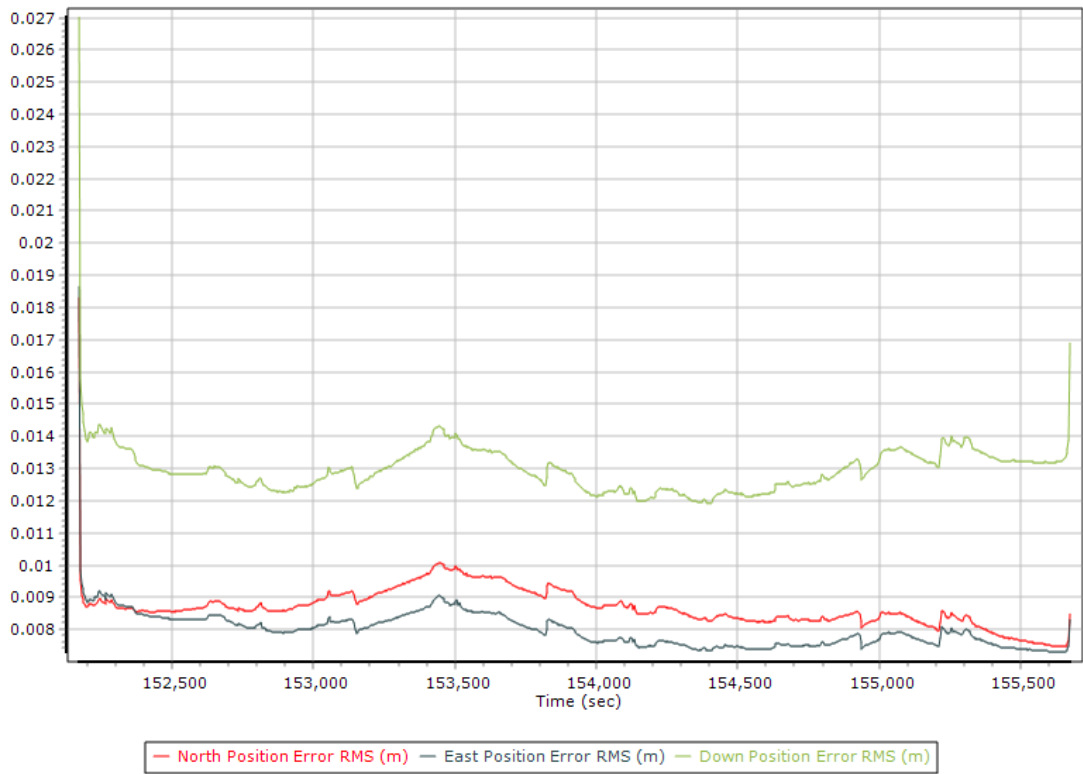


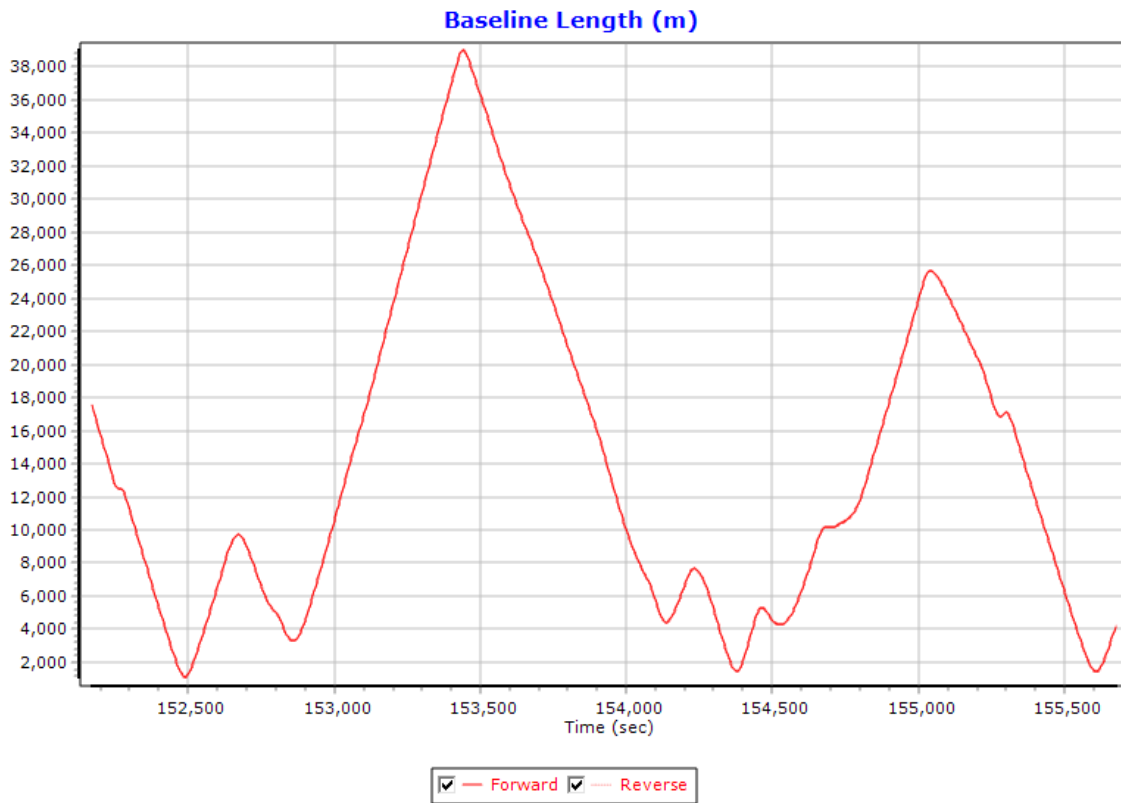
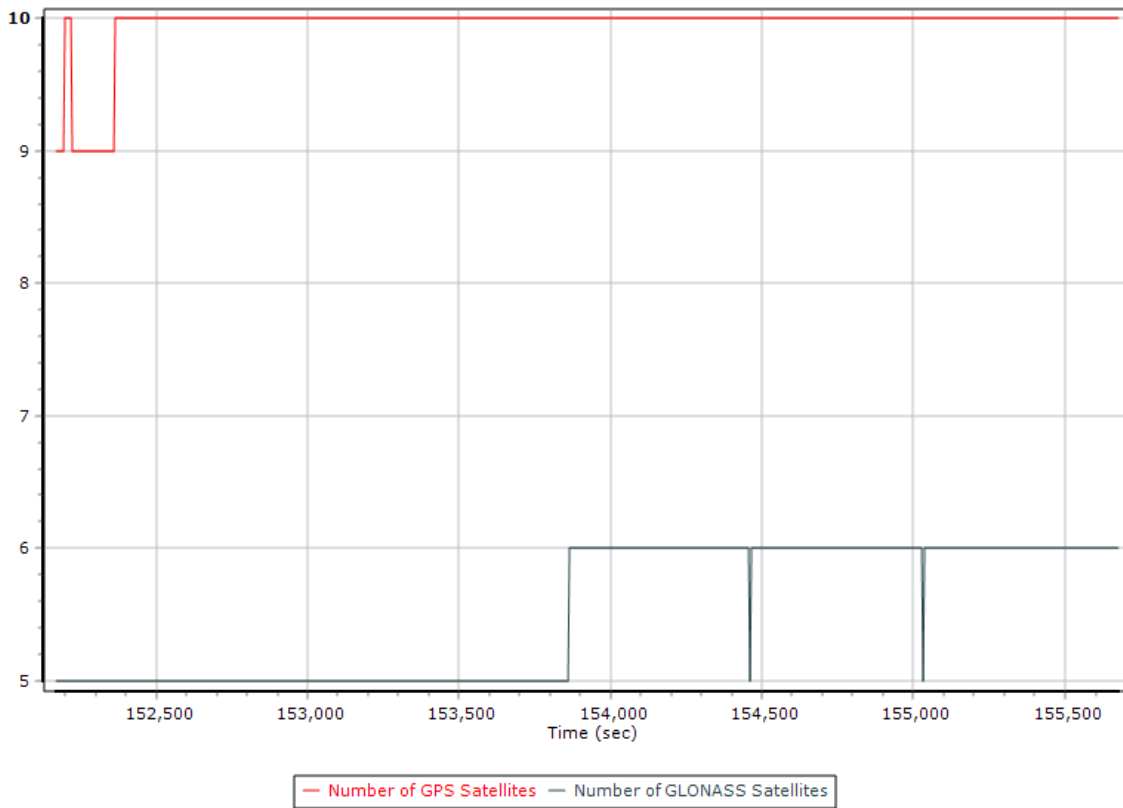
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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="3cm"/>		
	<3cm 10cm 50cm 1m 10m		

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

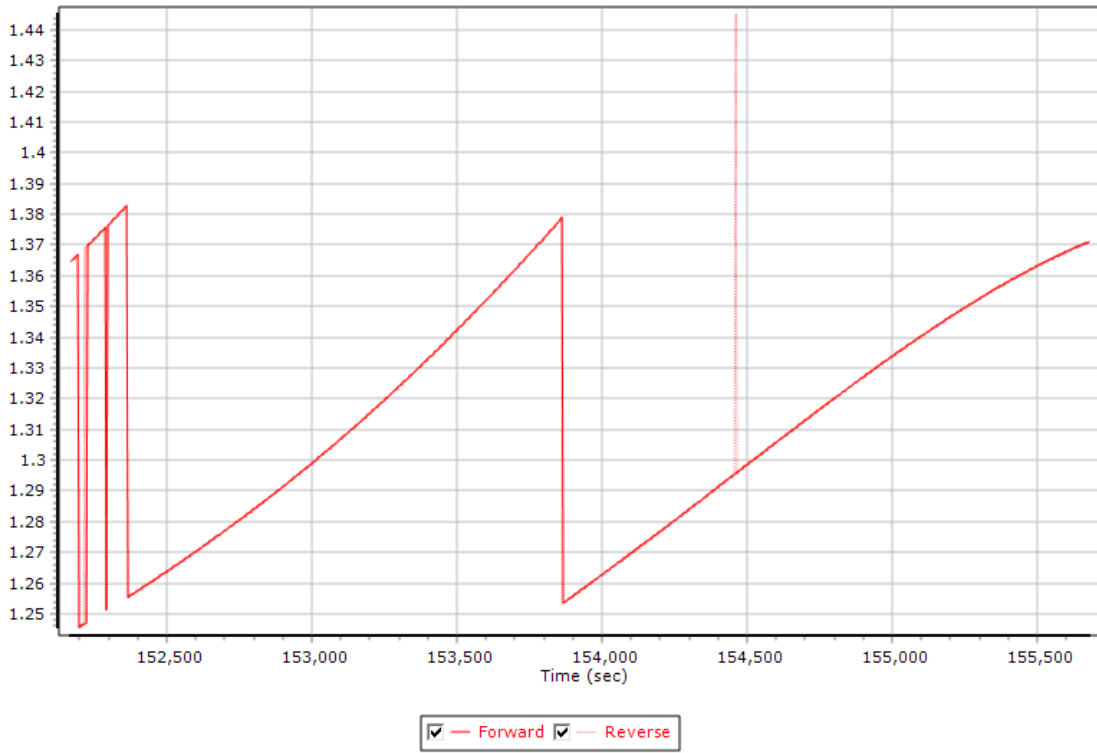
Timing	
Start	<input type="text" value="152168.382"/>
End	<input type="text" value="155679.203"/>
<input type="checkbox"/> Entire time interval	
<input checked="" type="checkbox"/> Seconds of start week	
UTC Offset	<input type="text" value="18.000"/>
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



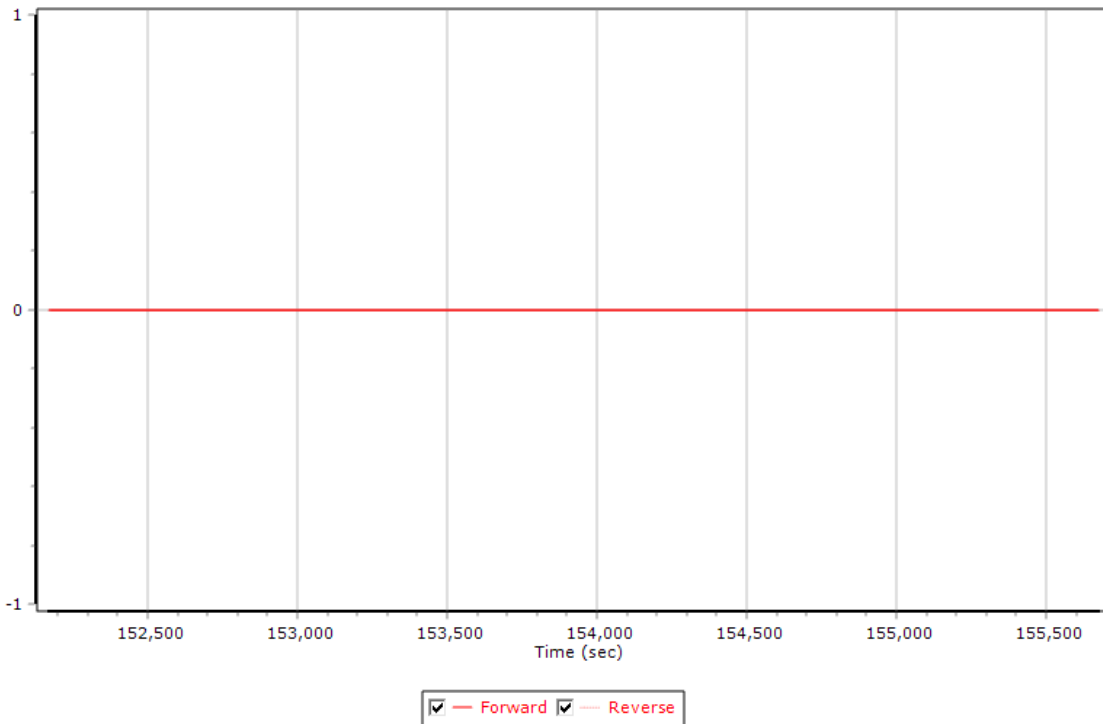




PDOP

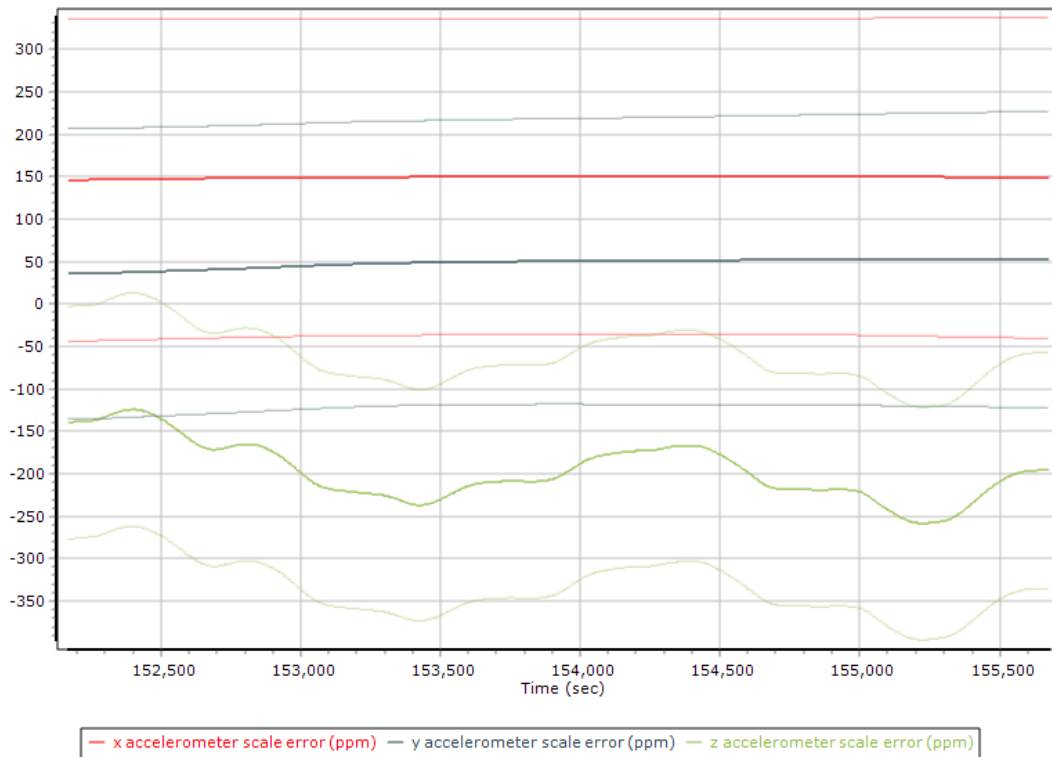
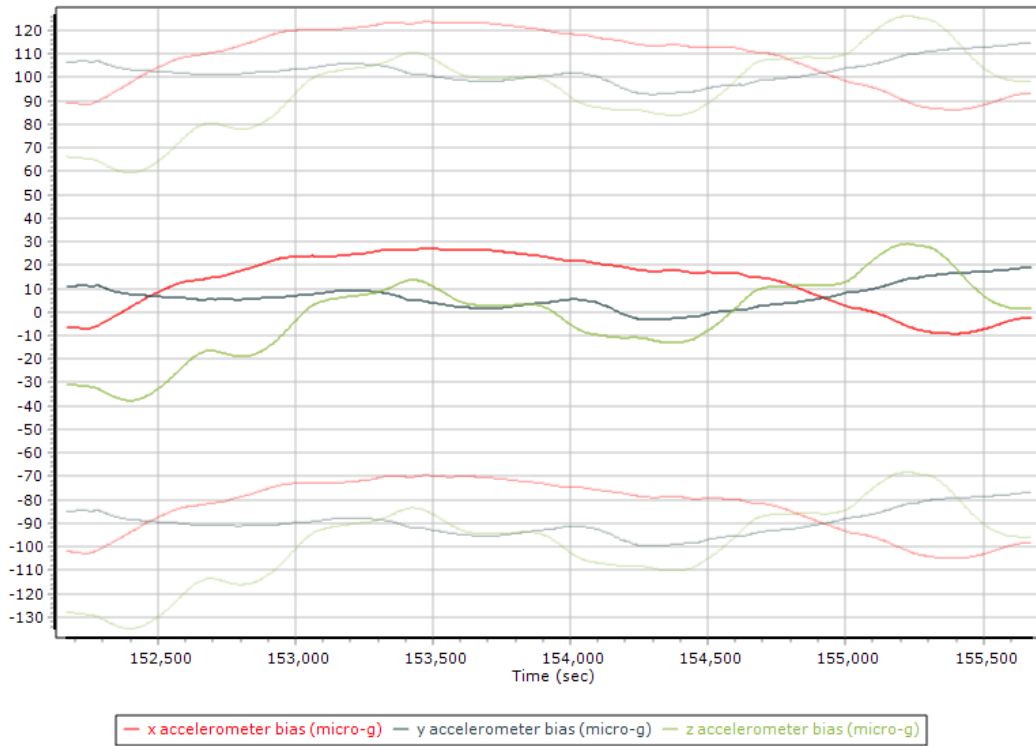


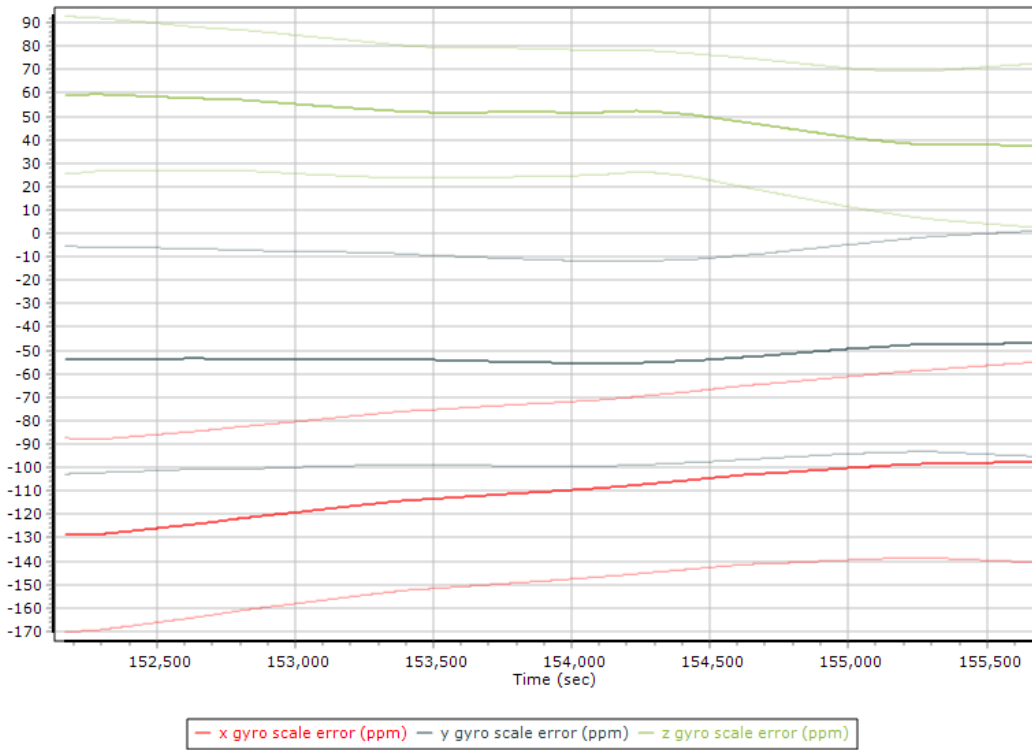
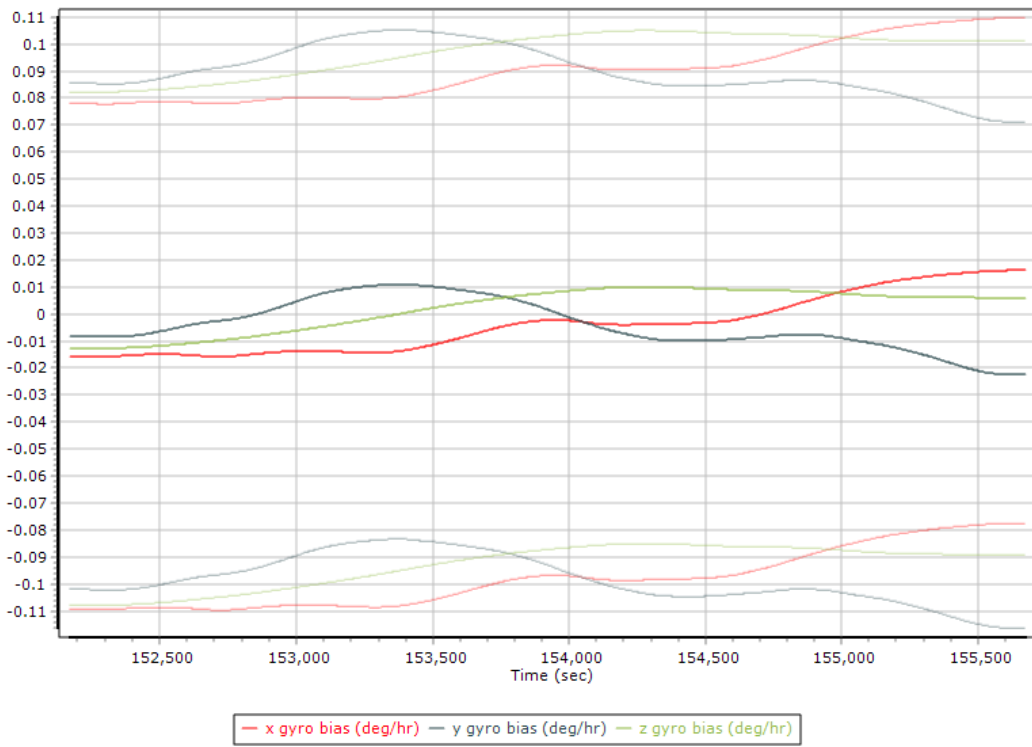
Processing mode



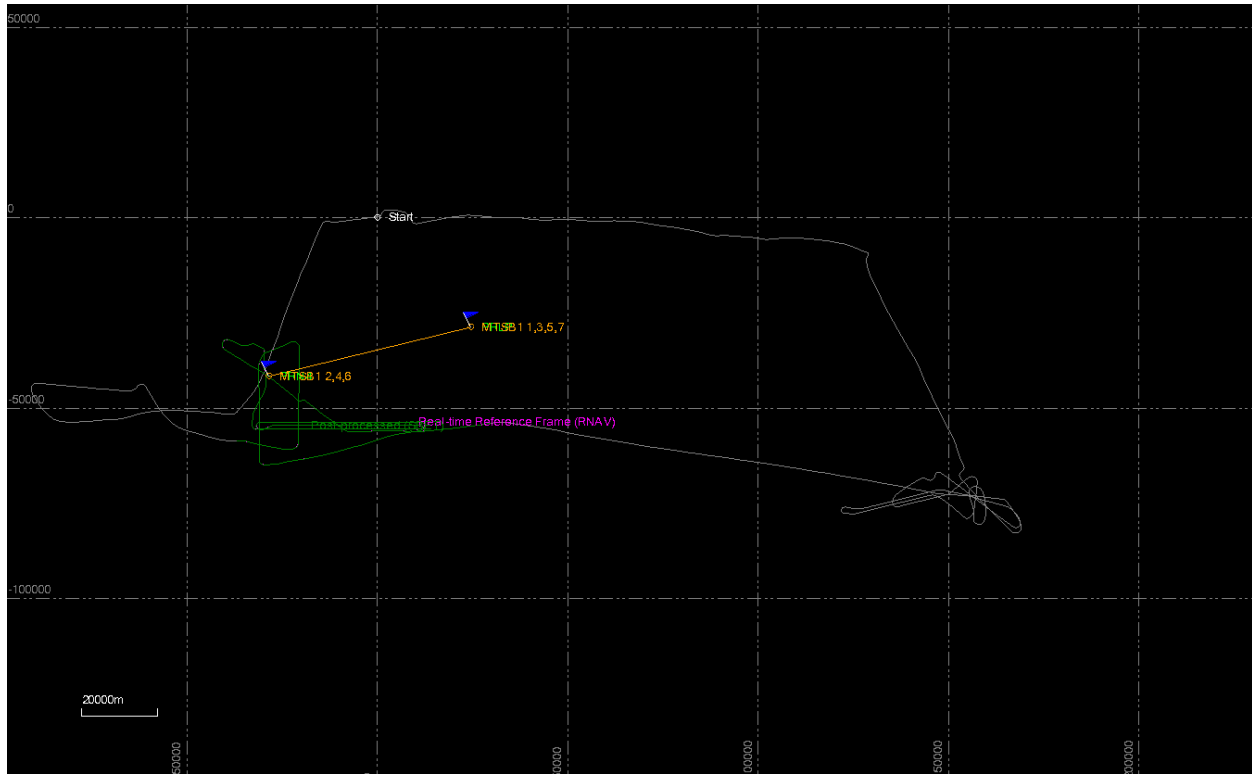
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





AZT18141B2



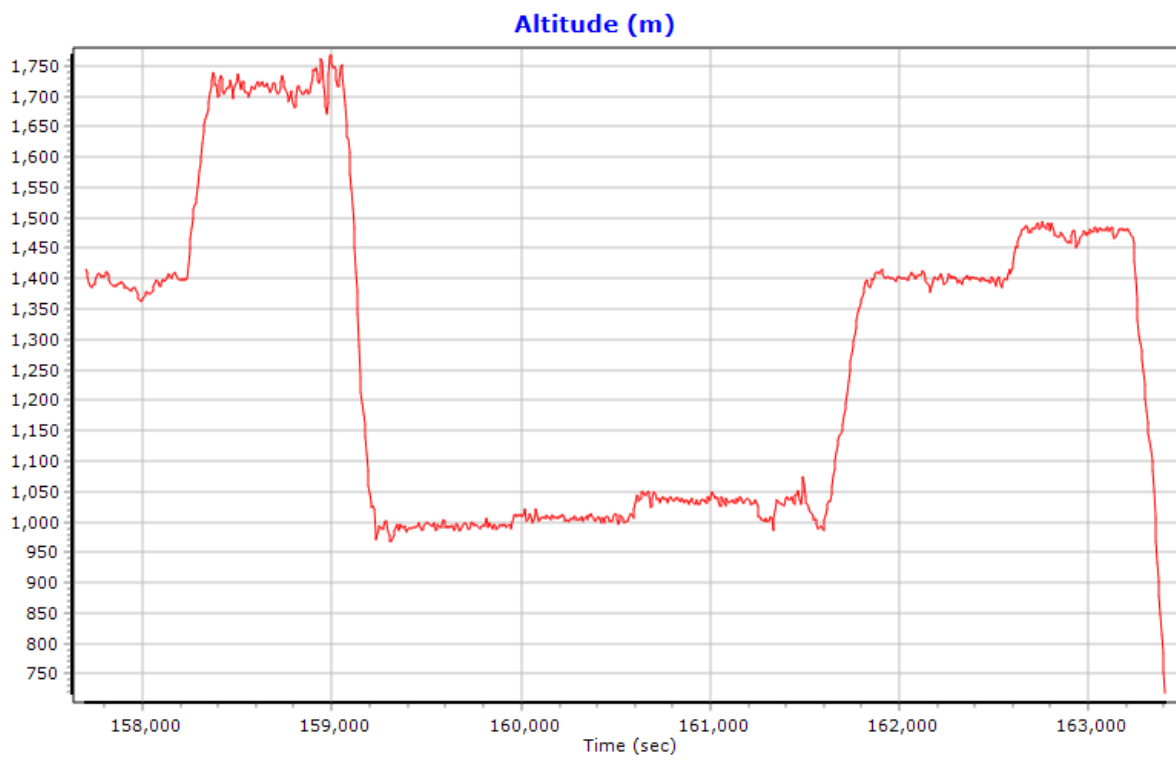
Stabilized Mount to IMU Lever Arm	Stabilized Mount to IMU Mounting Angles
X: -0.034 m	X: 0.000 deg
Y: -0.010 m	Y: 0.000 deg
Z: -0.352 m	Z: 0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	Aircraft to Stabilized Mount Mounting Angles
X: -0.049 m	X: 0.000 deg
Y: 0.003 m	Y: 0.000 deg
Z: -1.230 m	Z: 0.000 deg
Standard Deviation: <3cm 10cm 50cm 1m 10m	

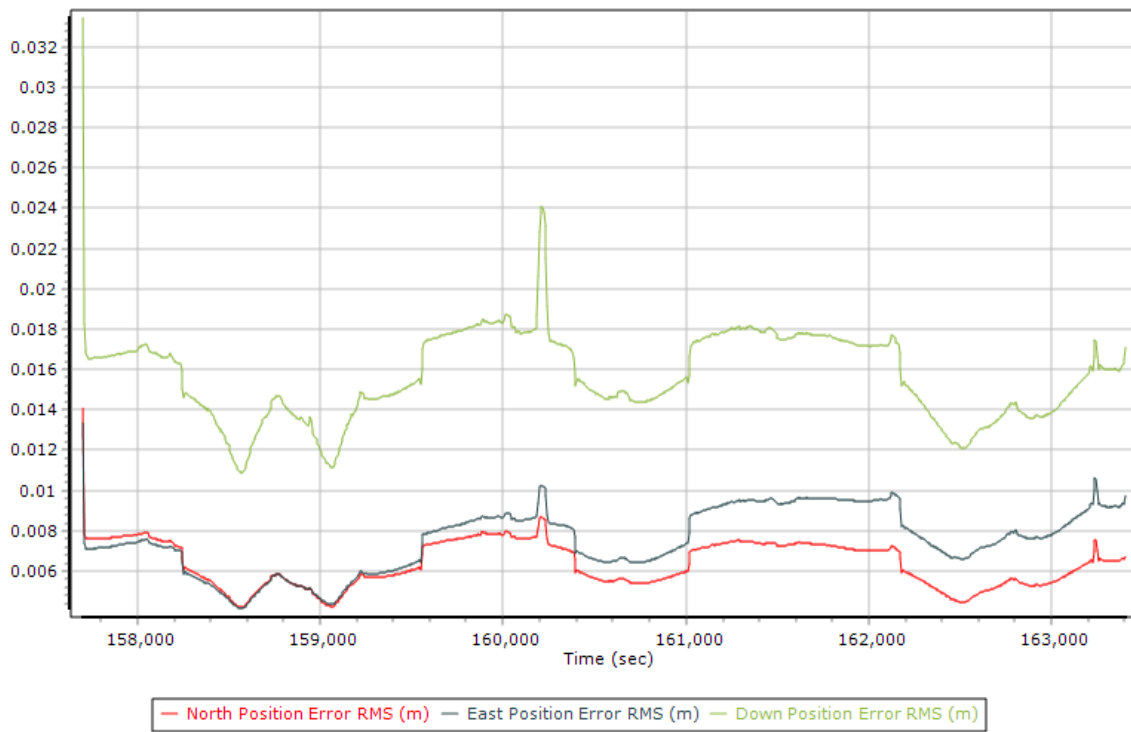
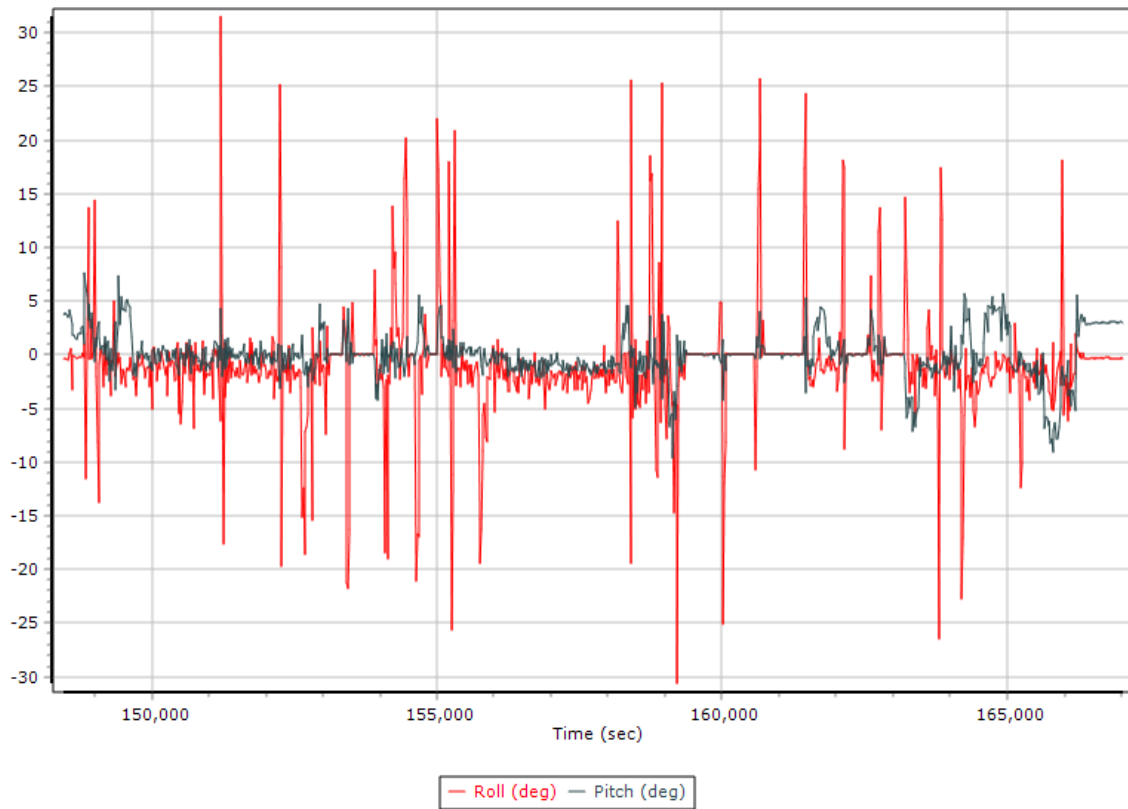
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

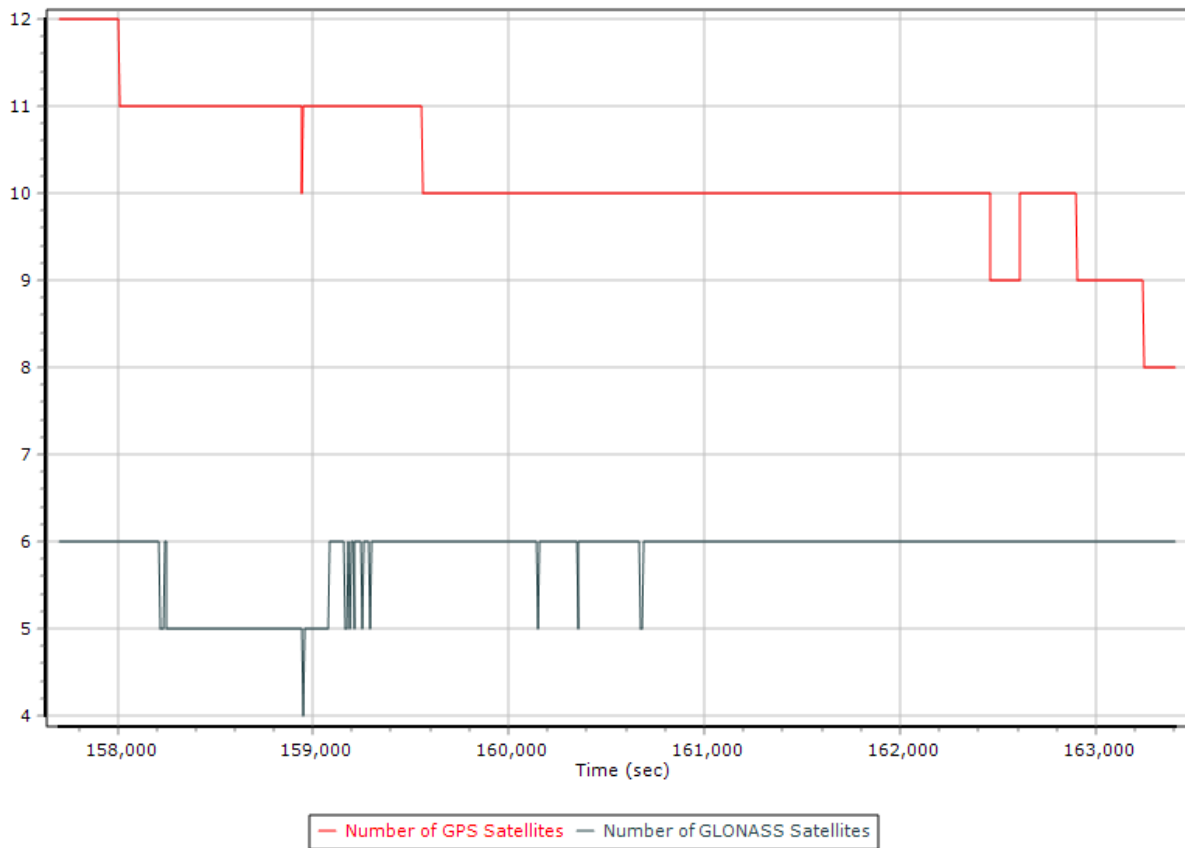
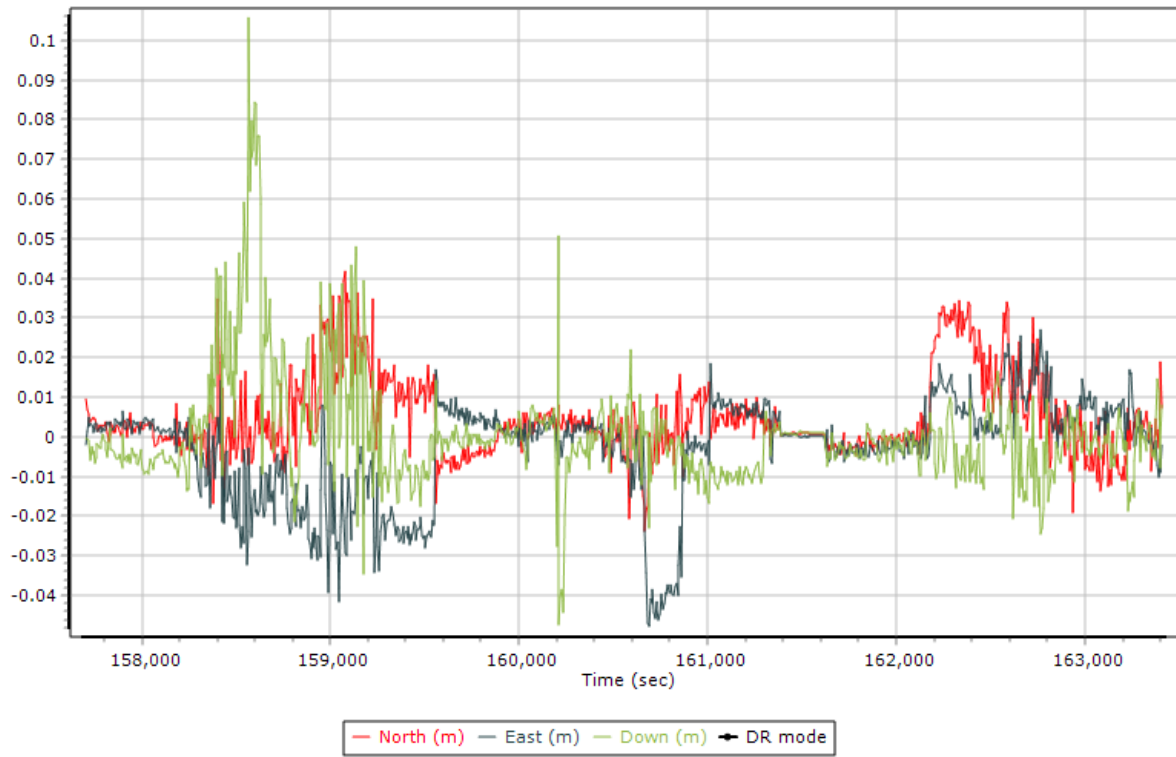
Timing

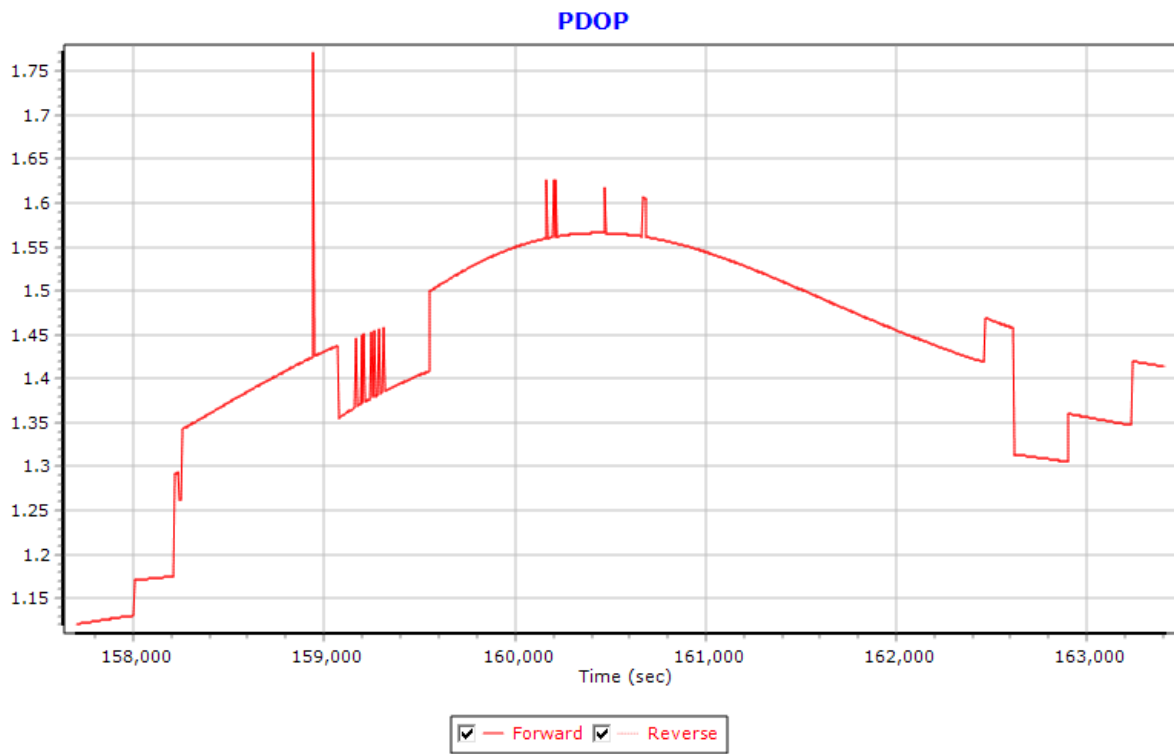
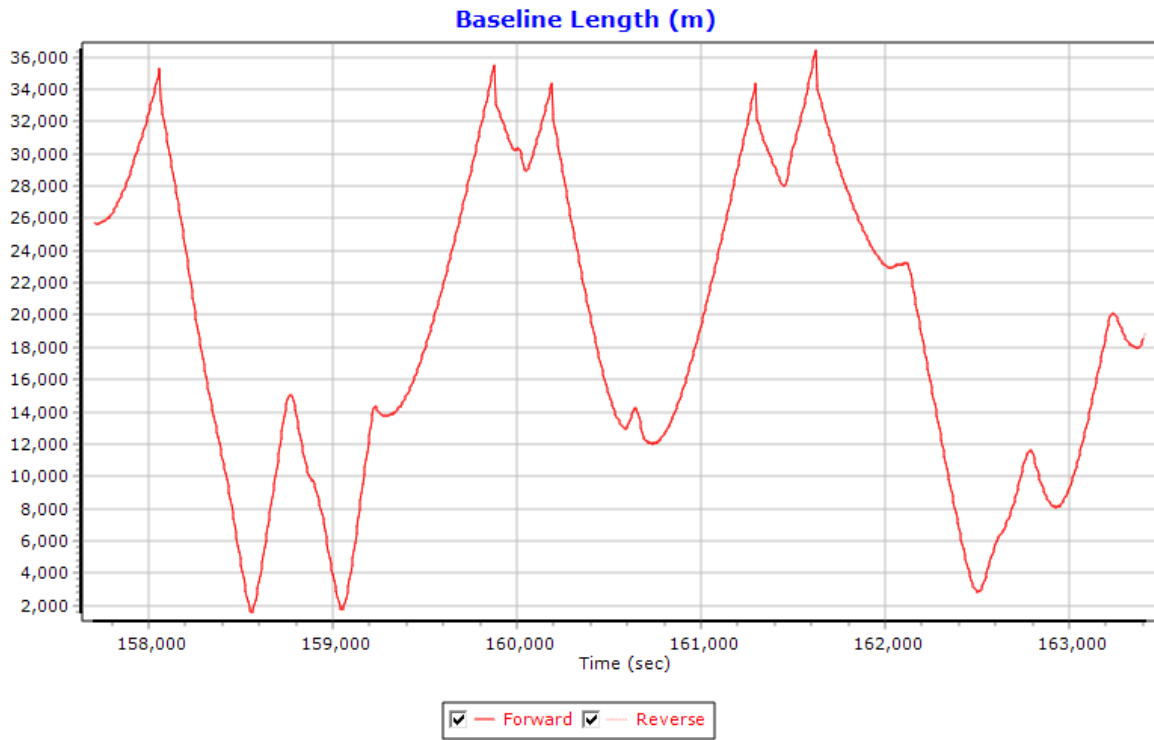
Start	157699.676	Data	Incr. (sec)
End	163411.007	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

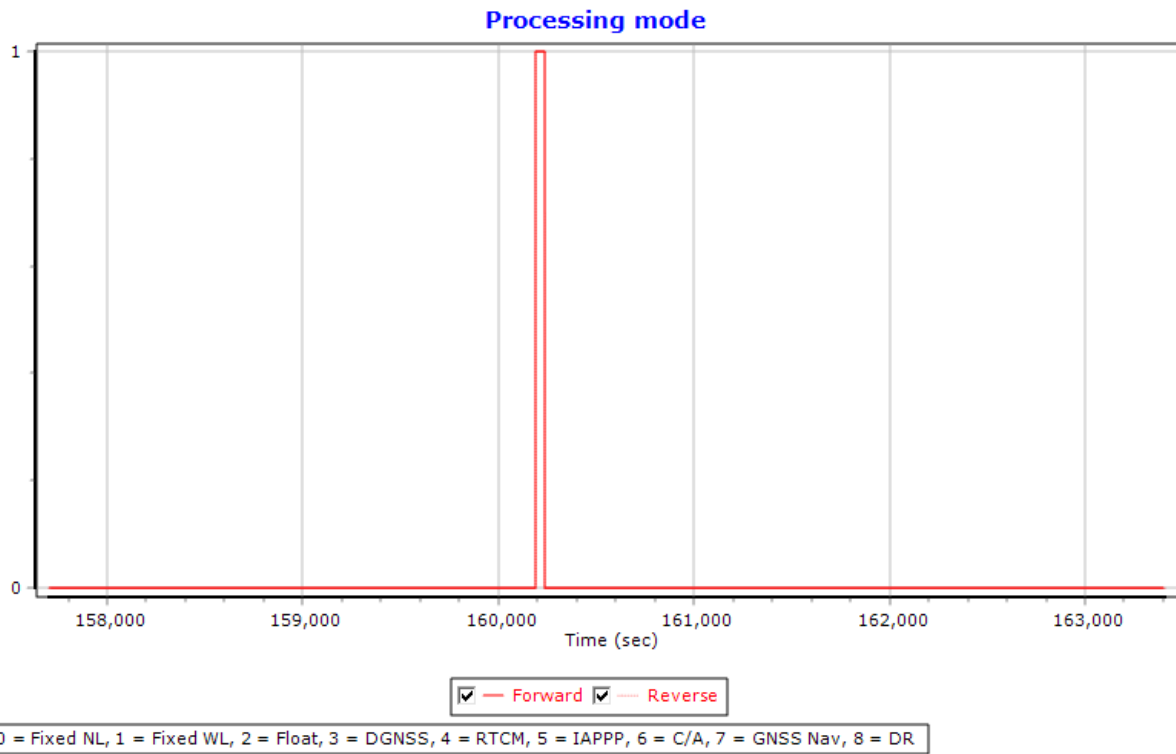
UTC Offset: 18.000



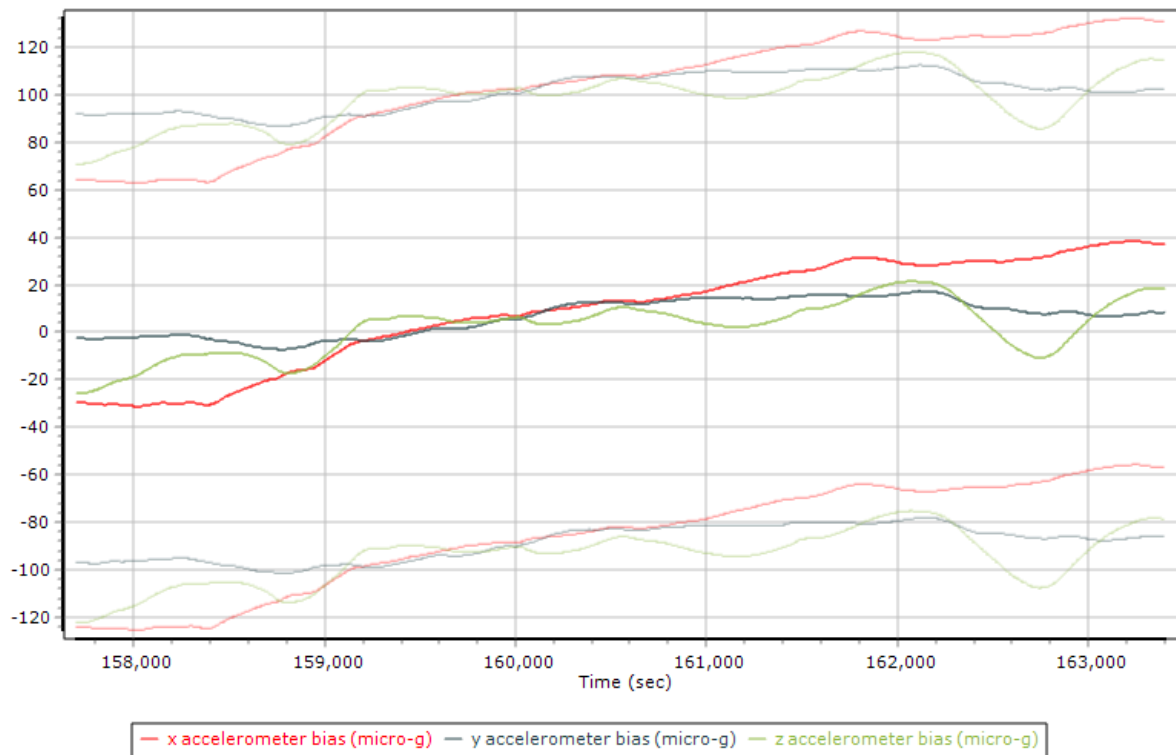


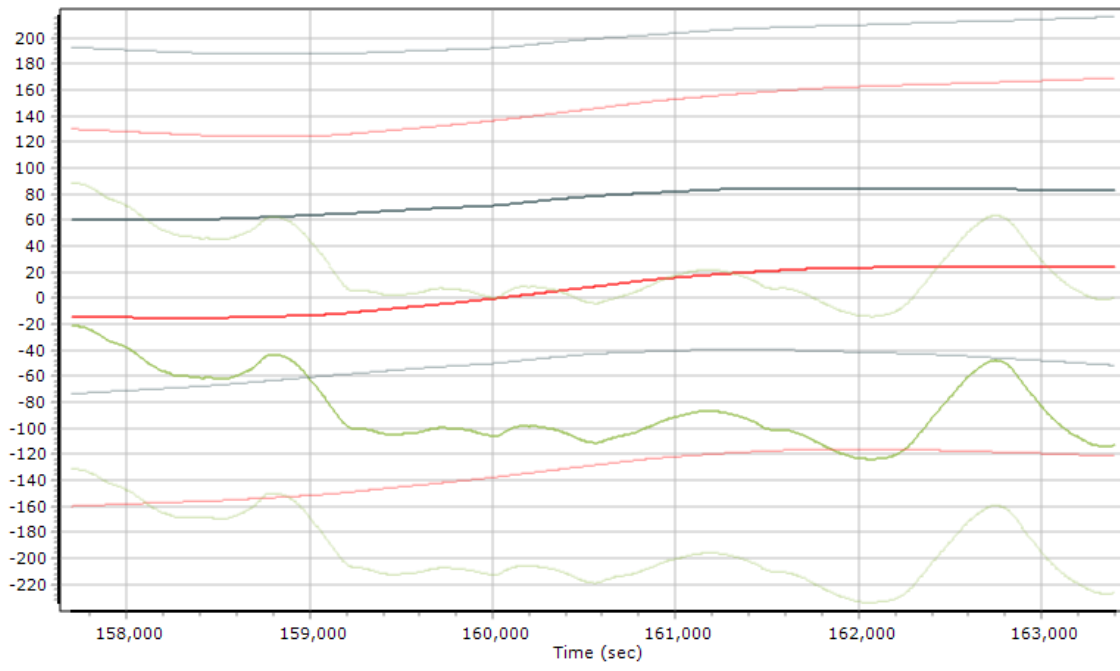




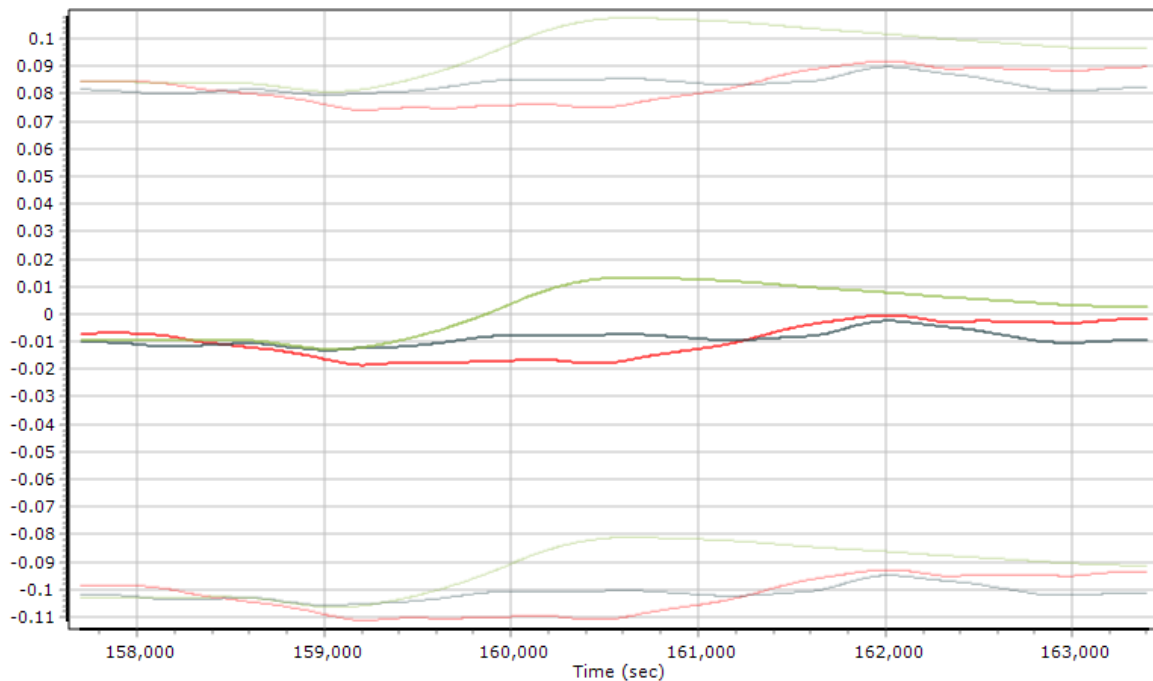


Sensor Errors

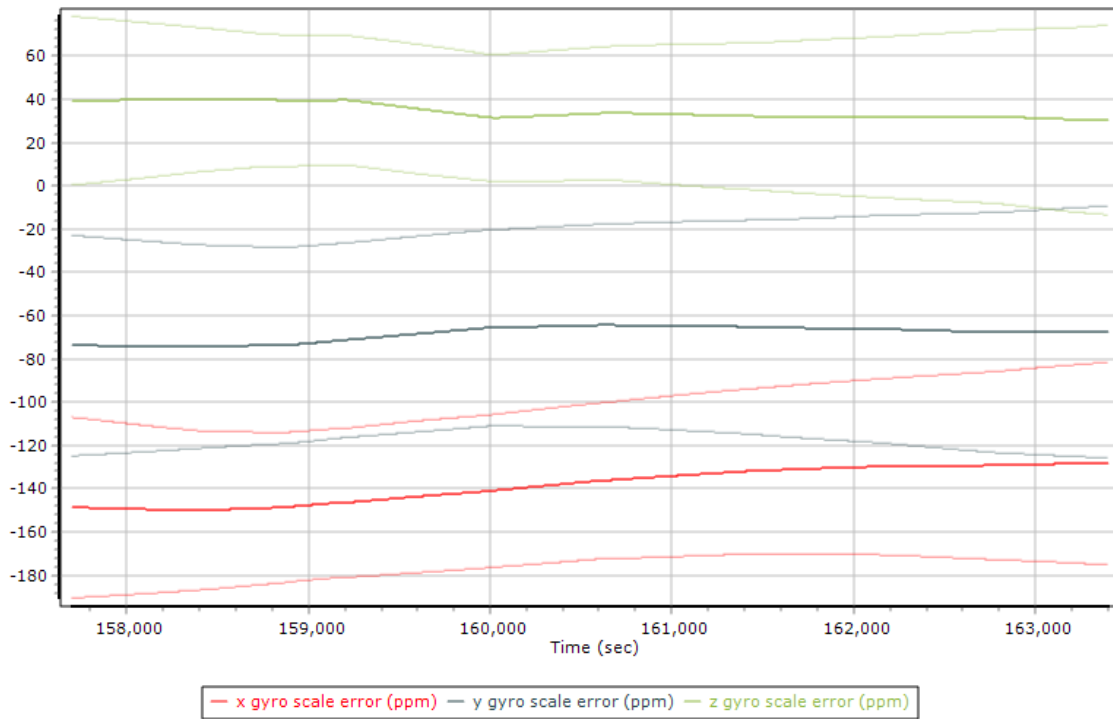




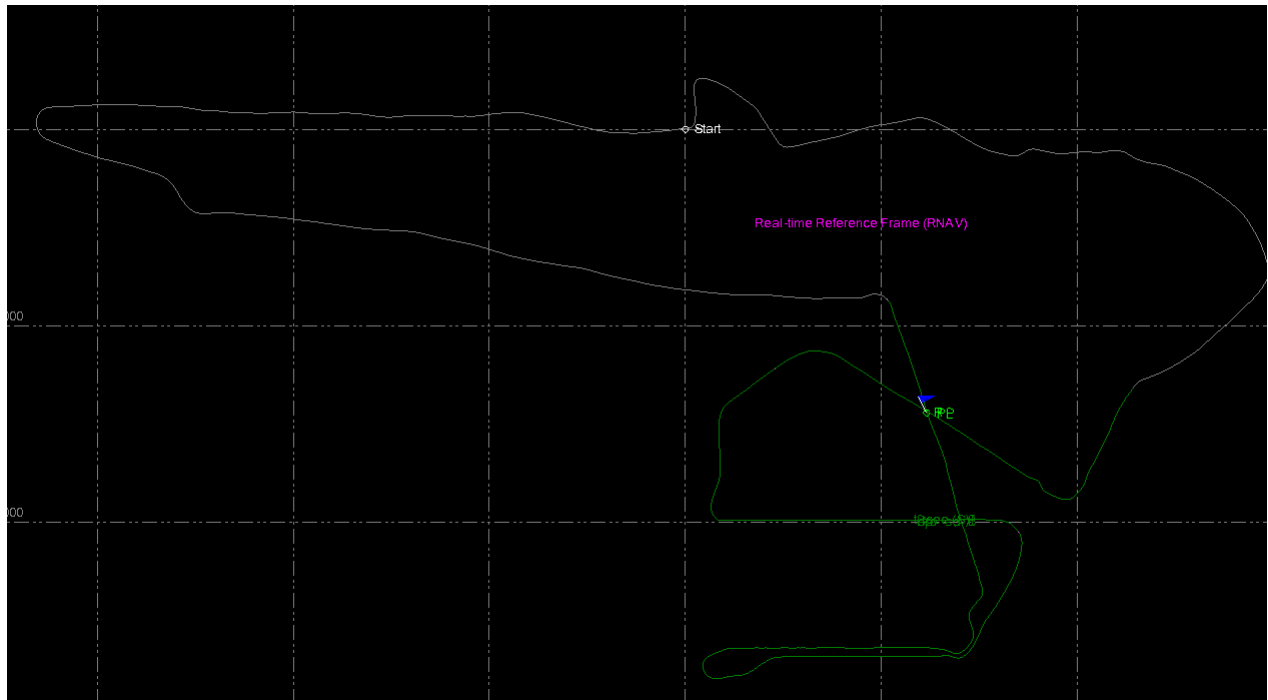
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



AZT18141C



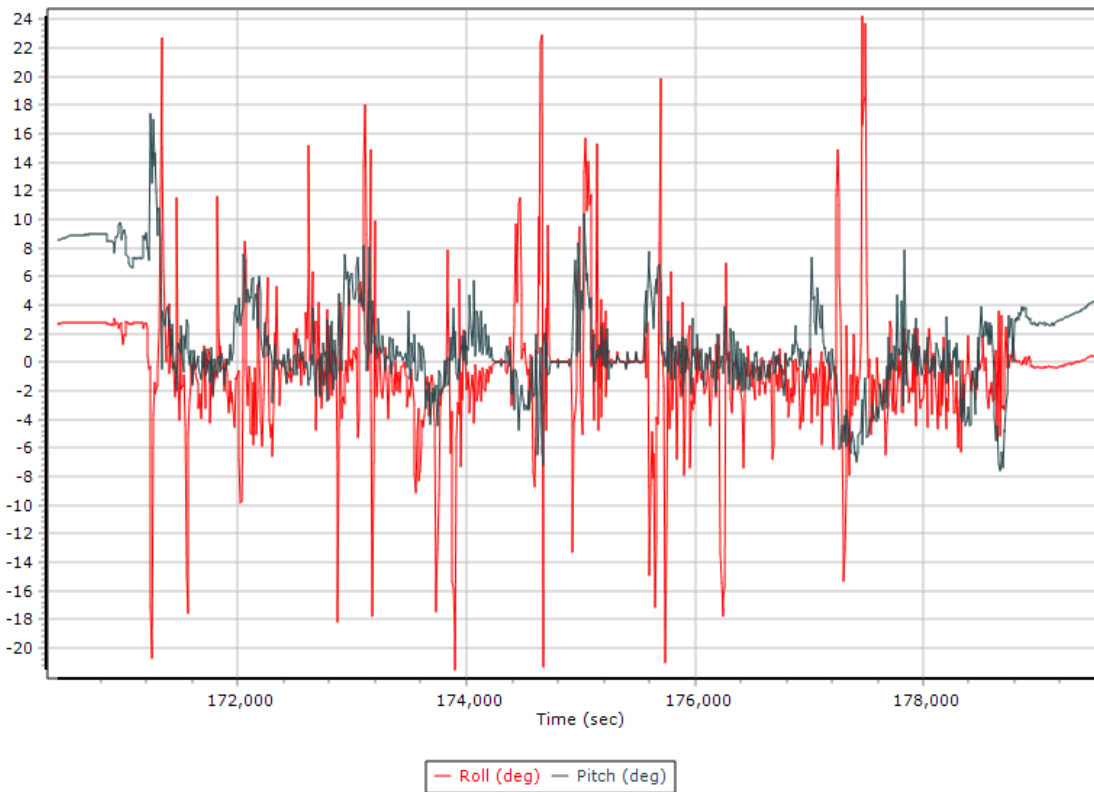
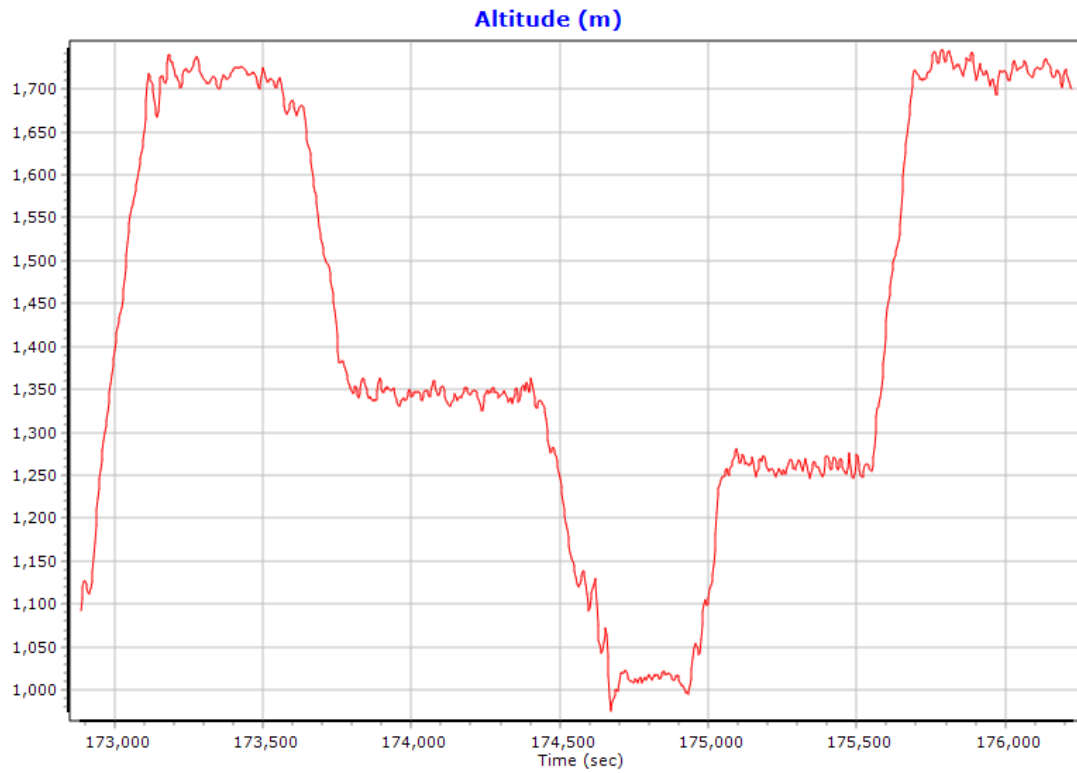
Timing

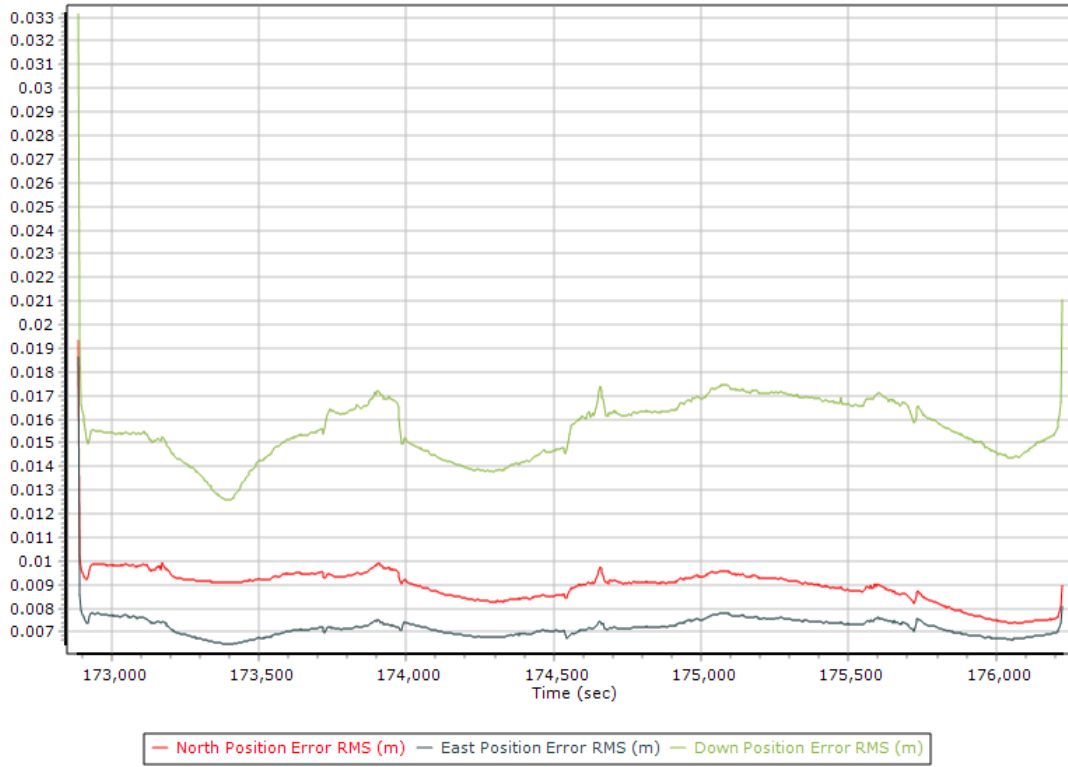
Start	<input type="text" value="172884.289"/>	Data	Incr. (sec)
End	<input type="text" value="176227.065"/>	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

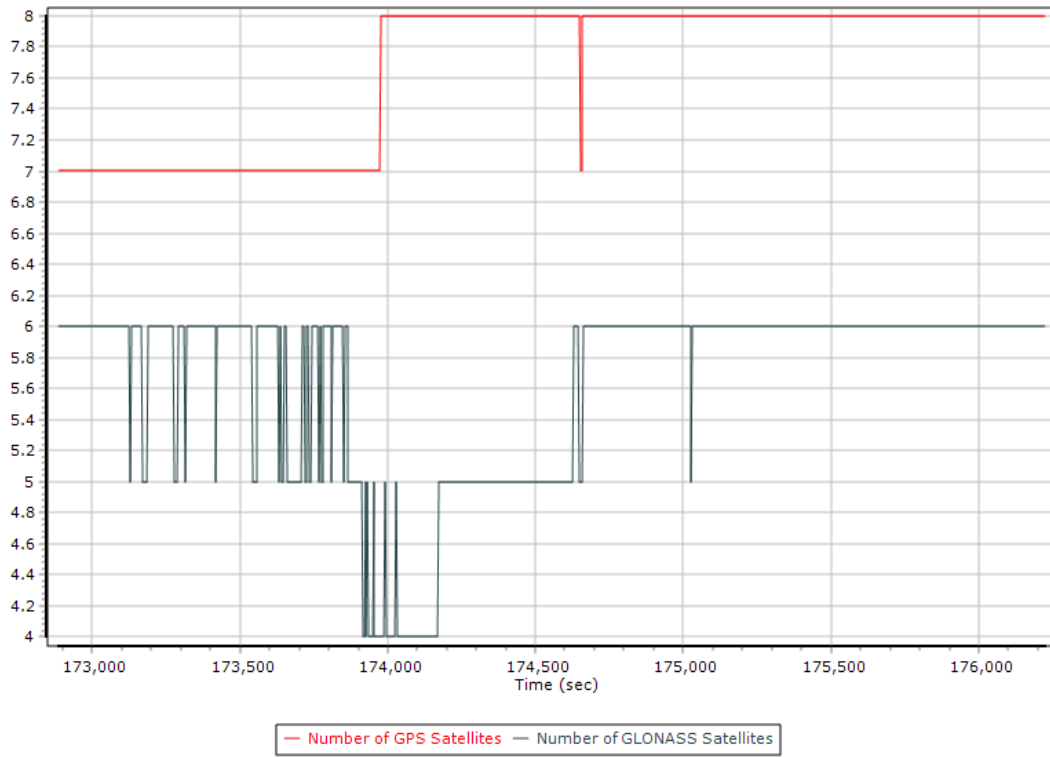
UTC Offset

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			

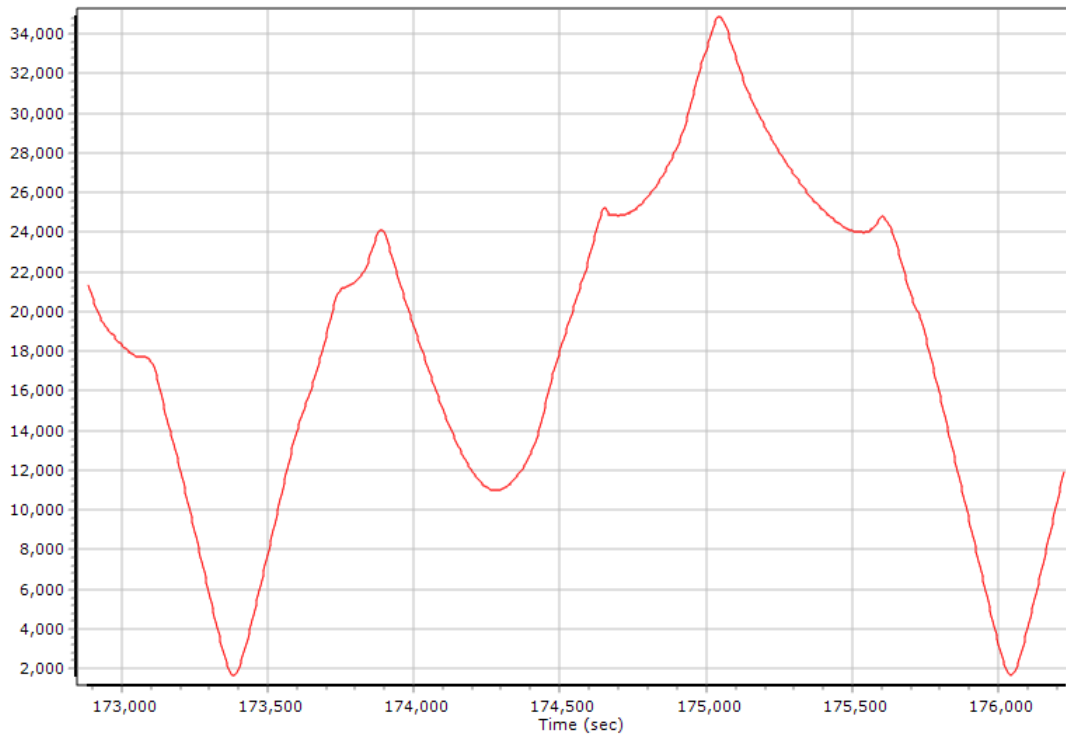
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

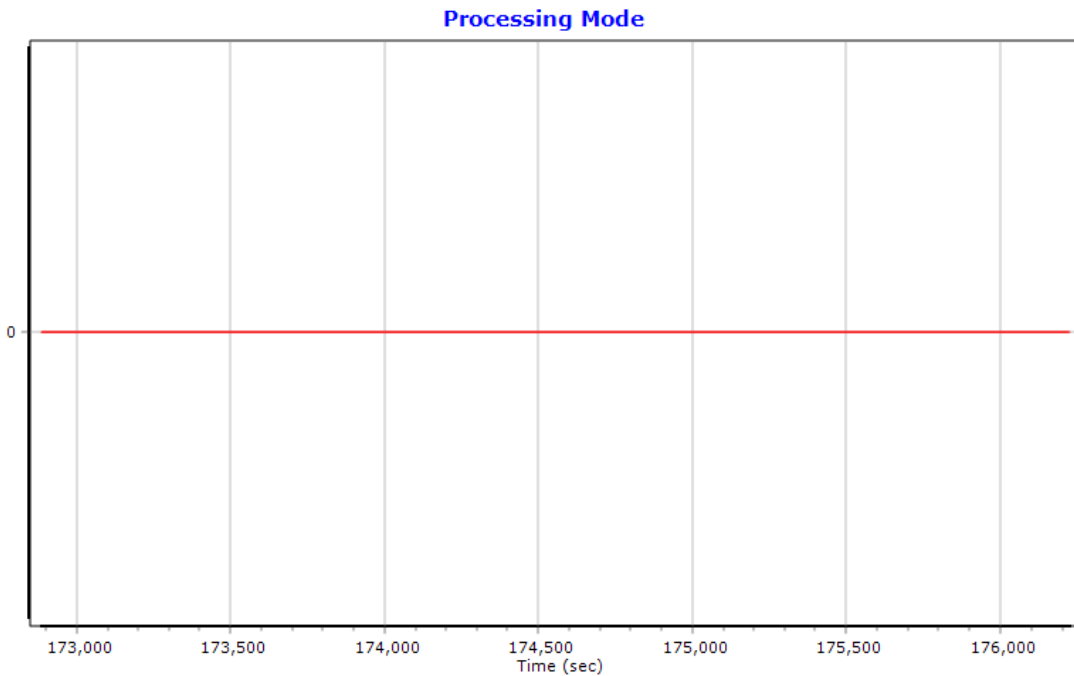
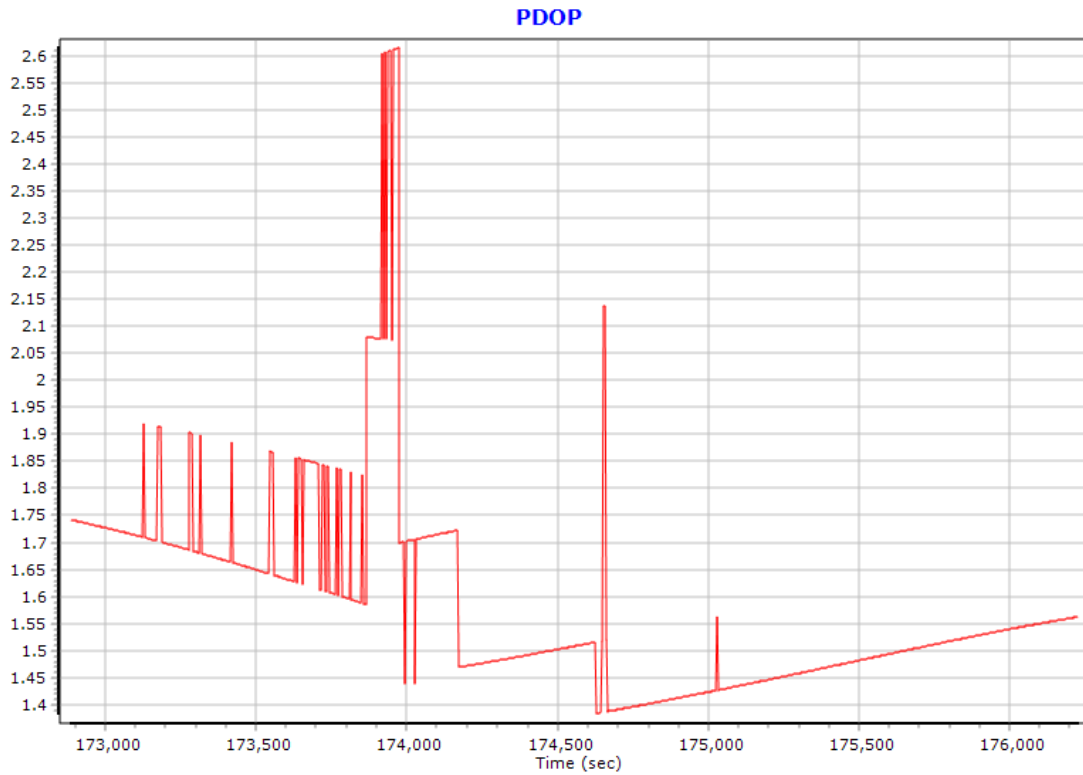






Baseline Length (m)

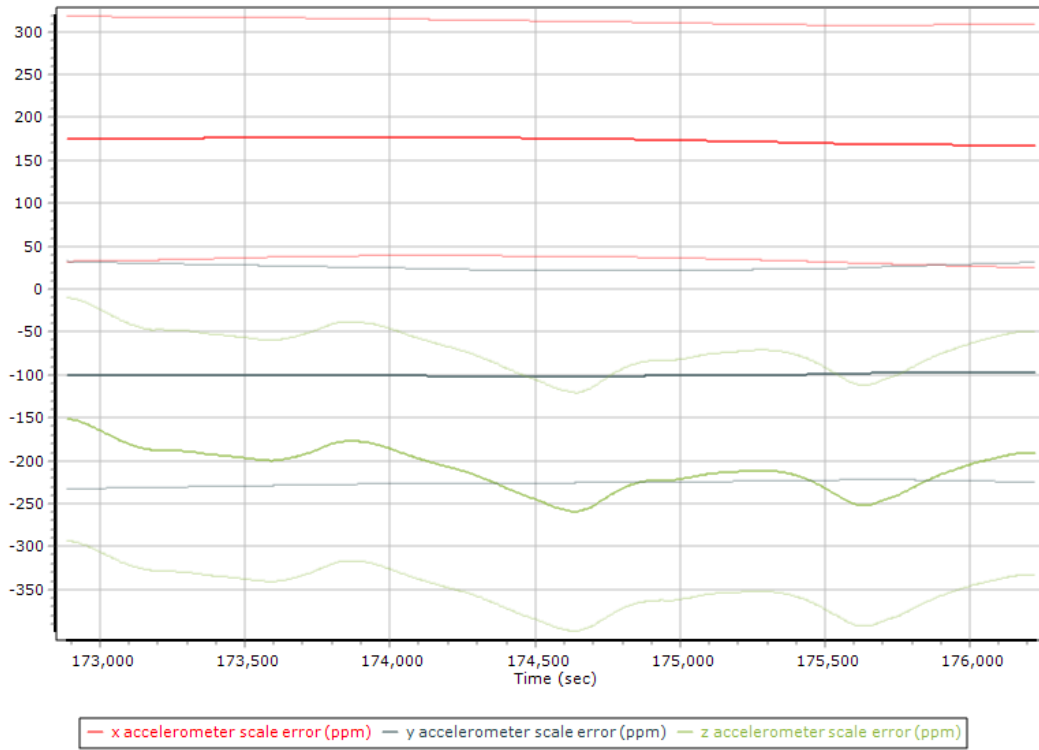
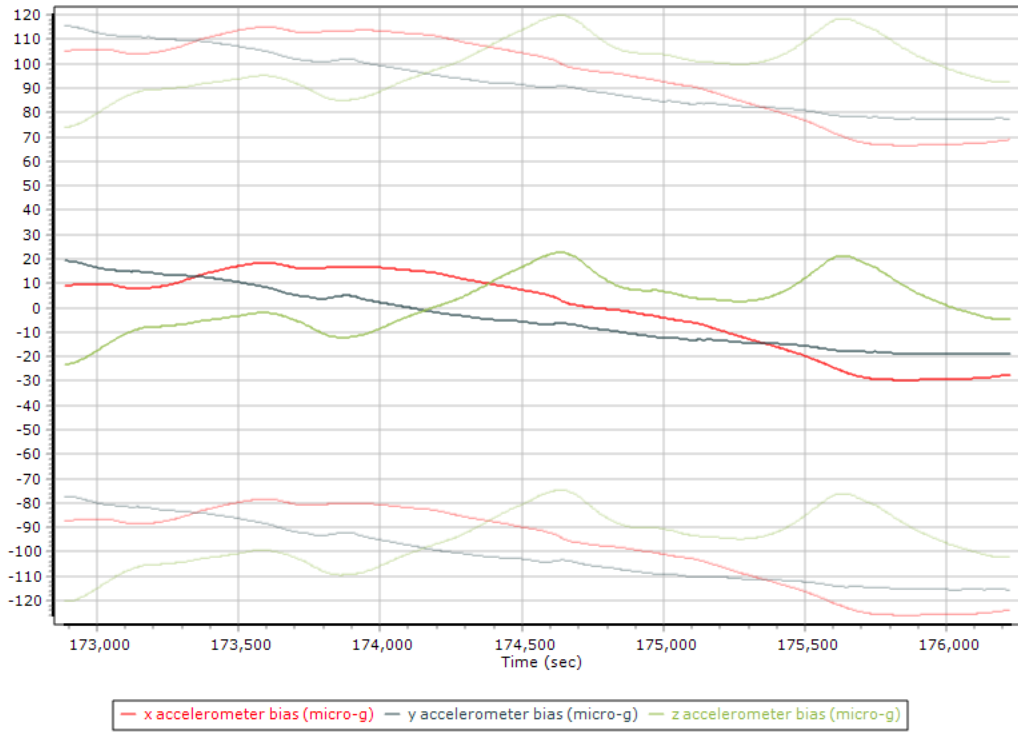


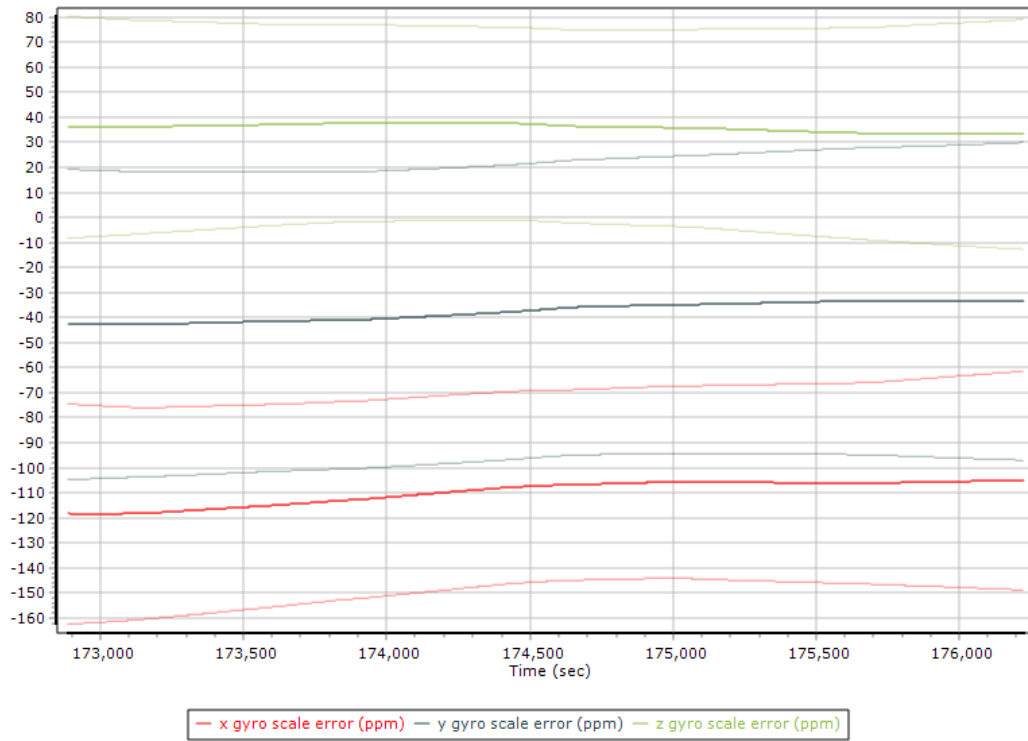
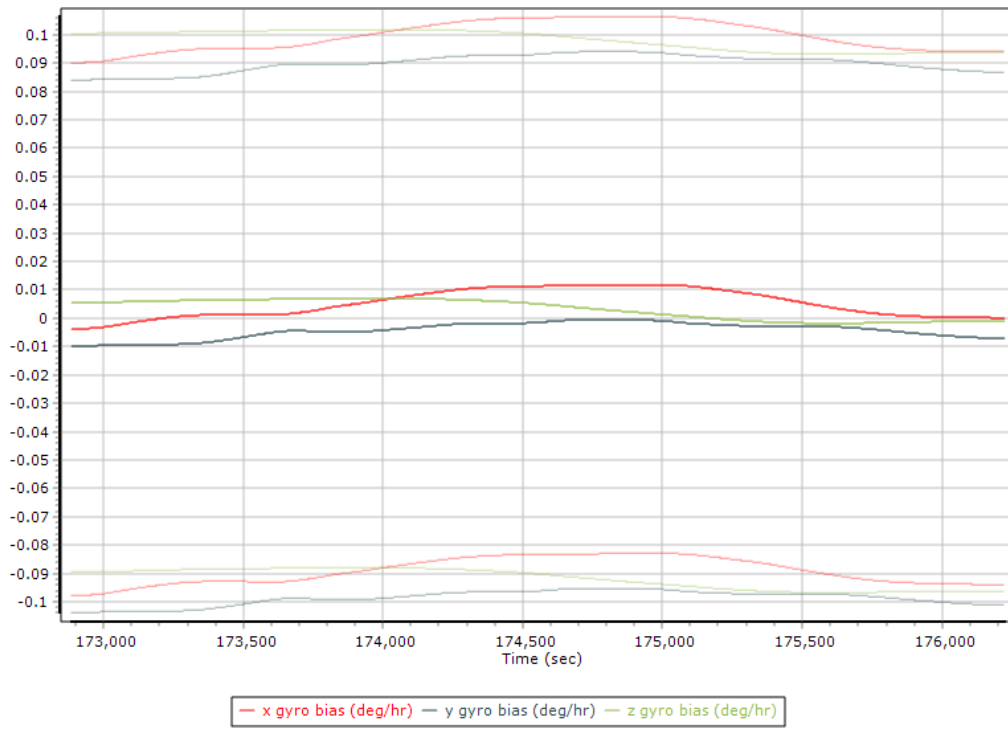


Forward Reverse

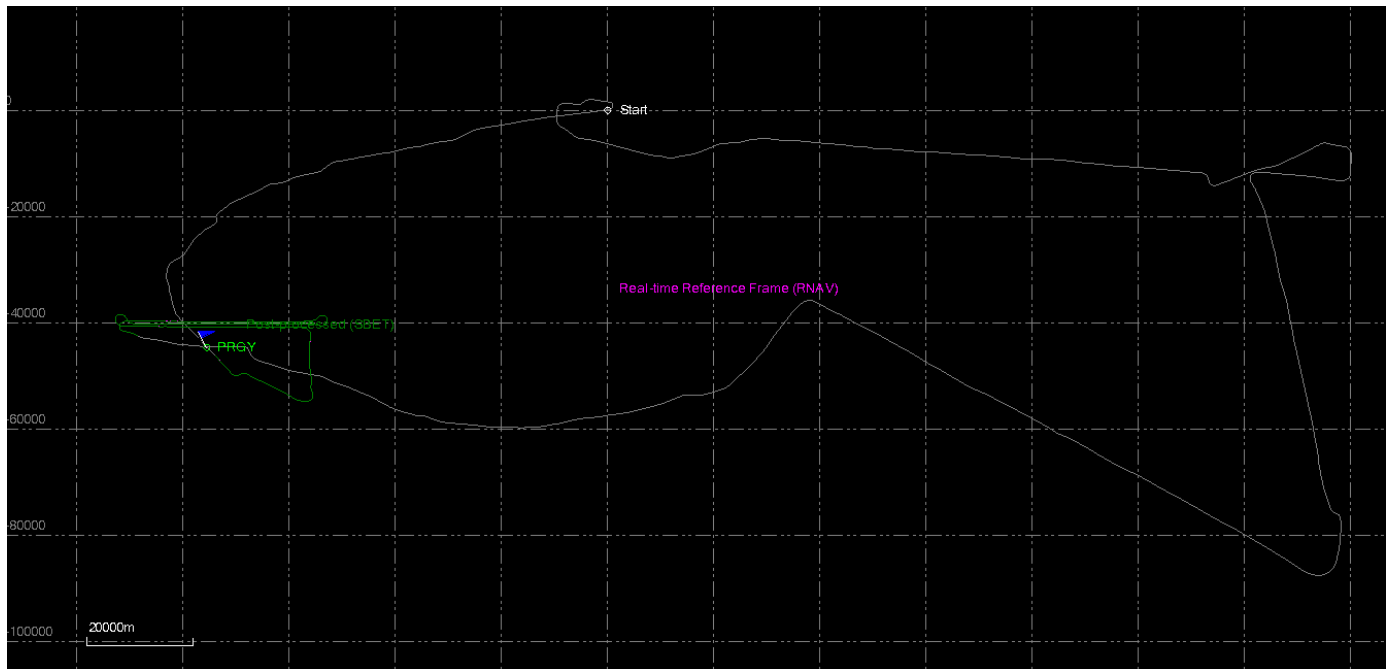
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors



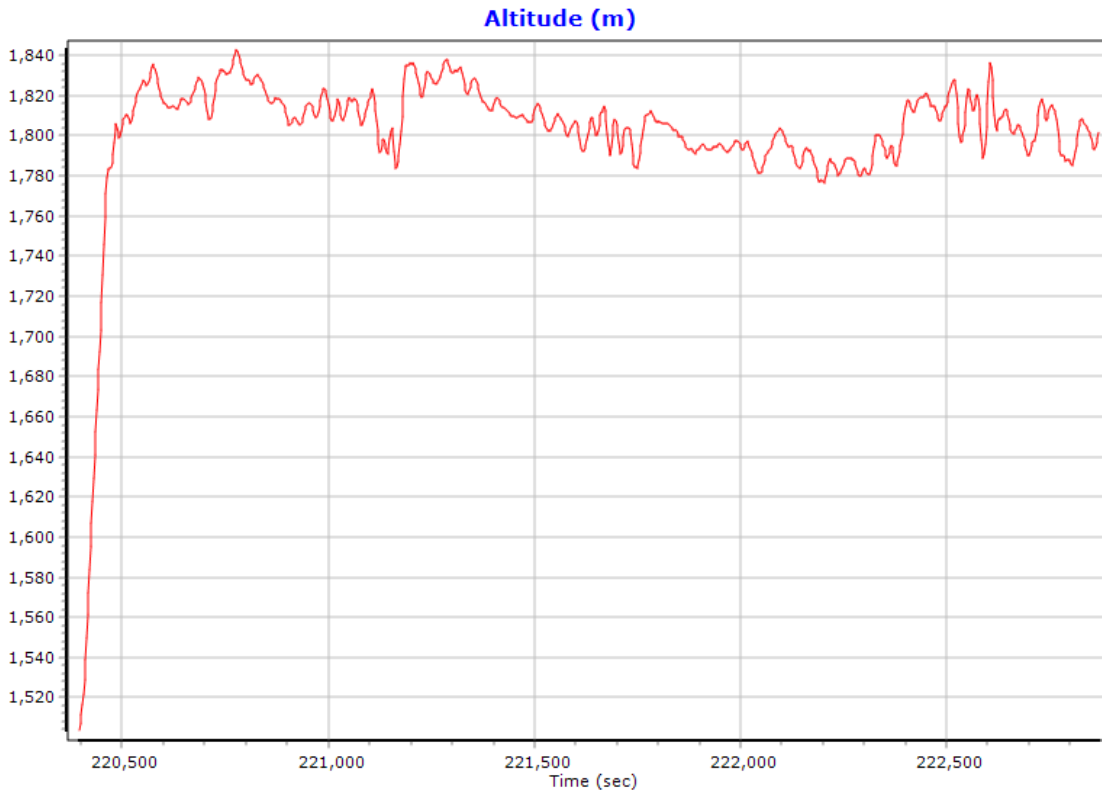


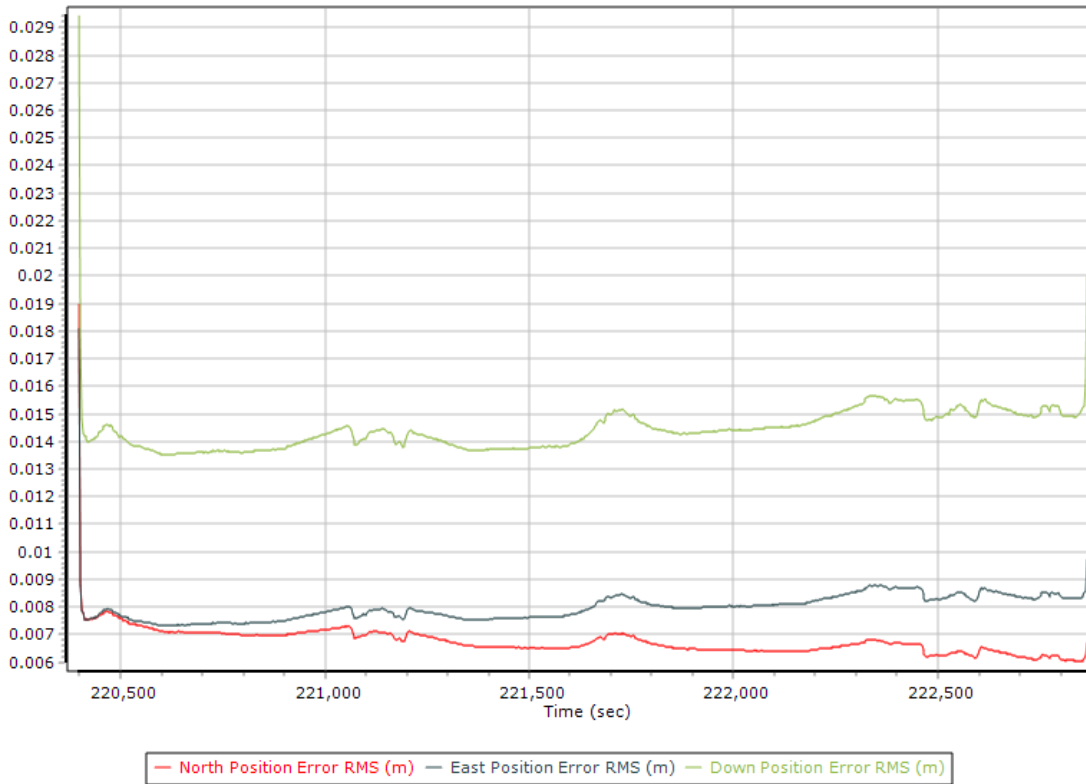
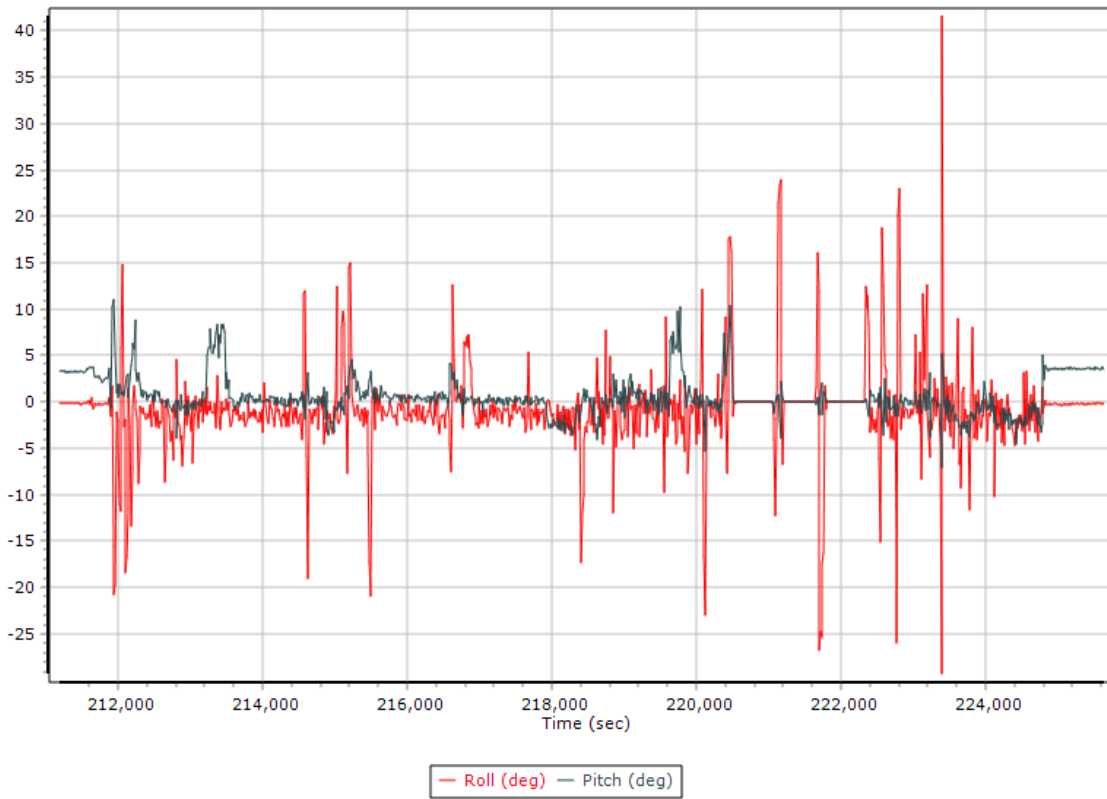
AZT18142A

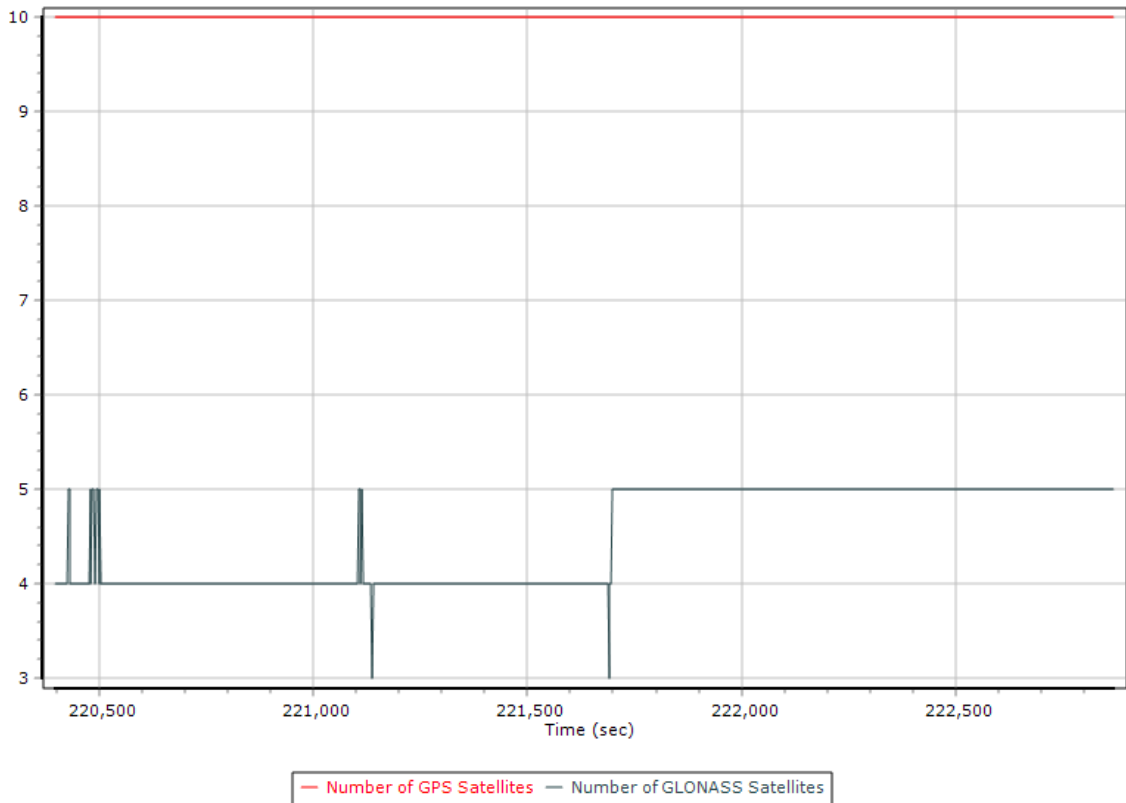
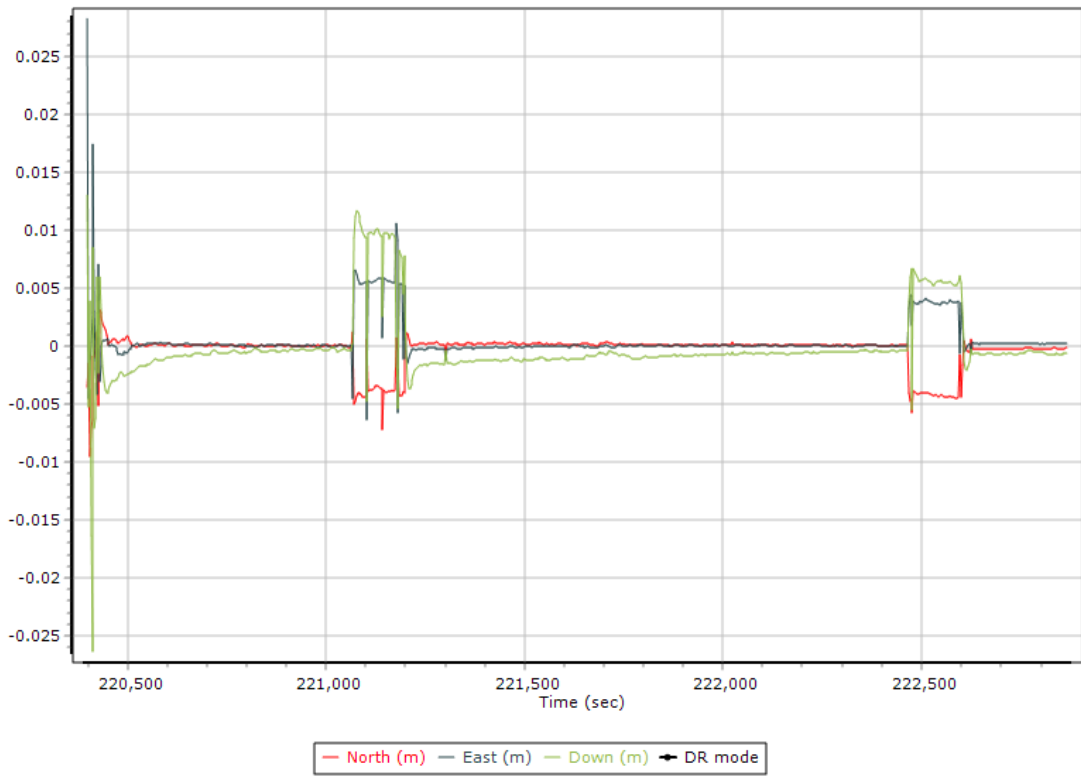


Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	-0.034 m	X	0.000 deg
Y	-0.010 m	Y	0.000 deg
Z	-0.352 m	Z	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm		Aircraft to Stabilized Mount Mounting Angles	
X	-0.049 m	X	0.000 deg
Y	0.003 m	Y	0.000 deg
Z	-1.230 m	Z	0.000 deg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

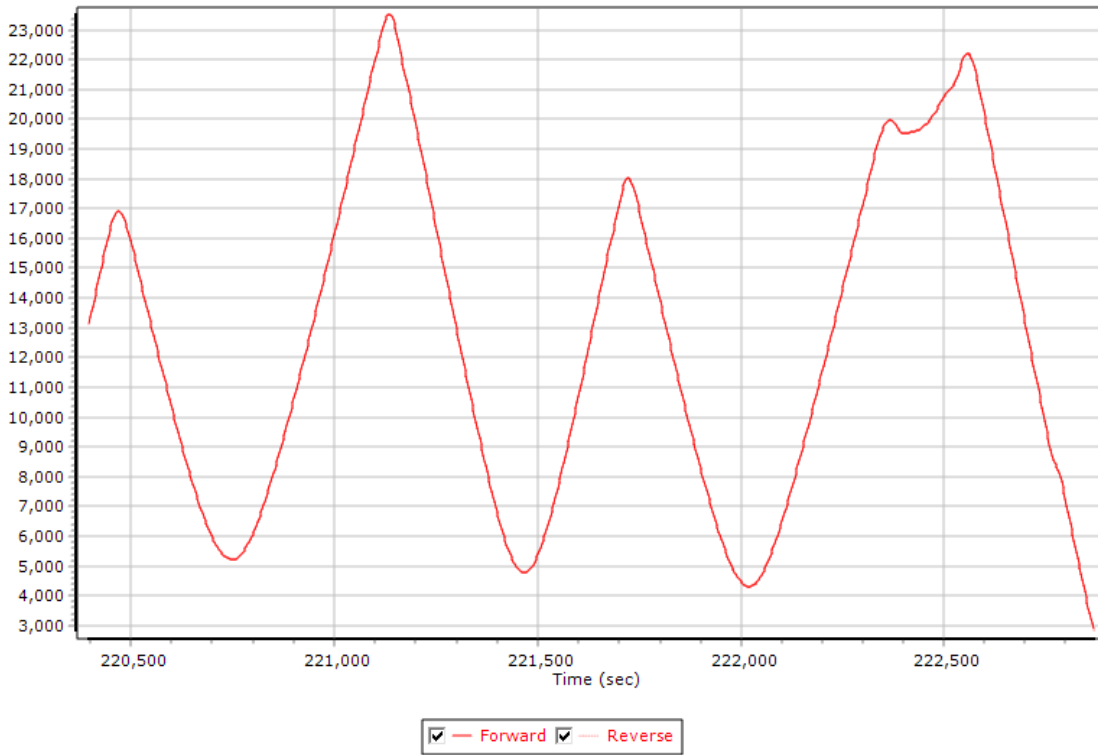
Timing	
Start	220395.080
End	222870.657
<input type="checkbox"/> Entire time interval <input checked="" type="checkbox"/> Seconds of start week	
UTC Offset	18.000
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



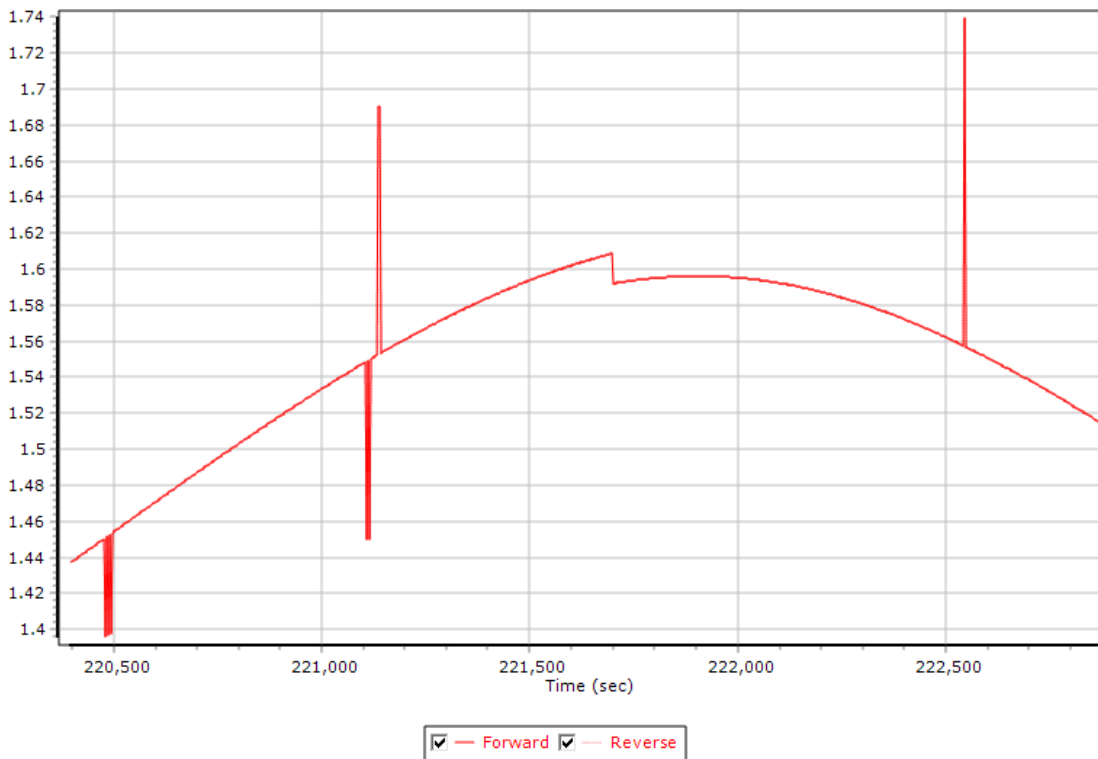


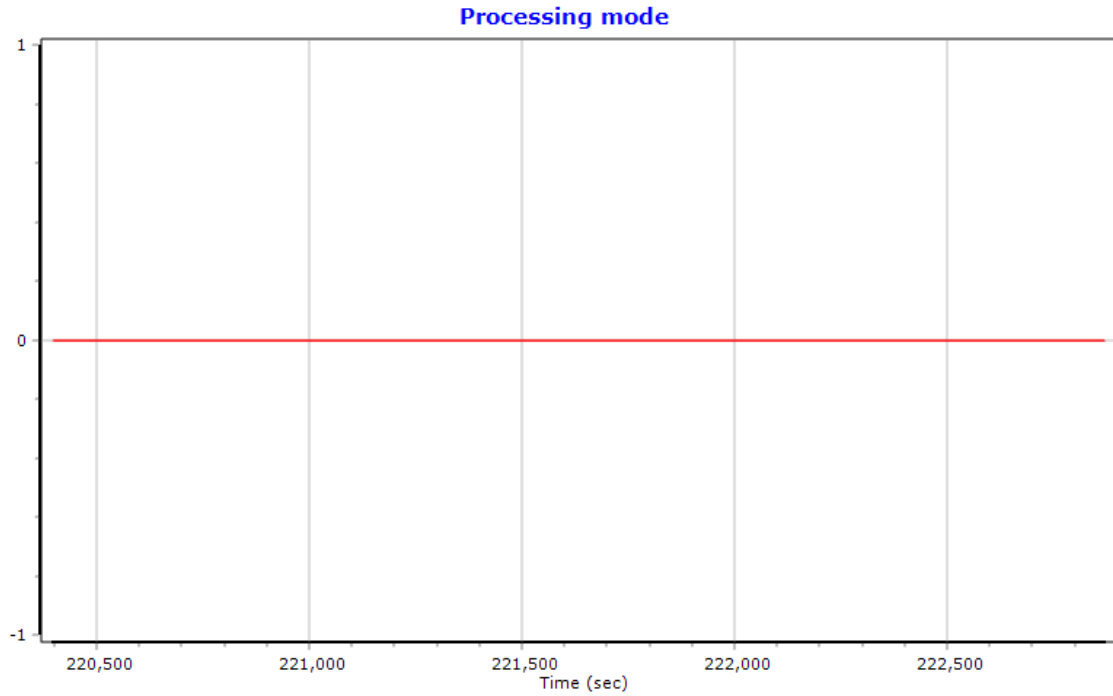


Baseline Length (m)



PDOP

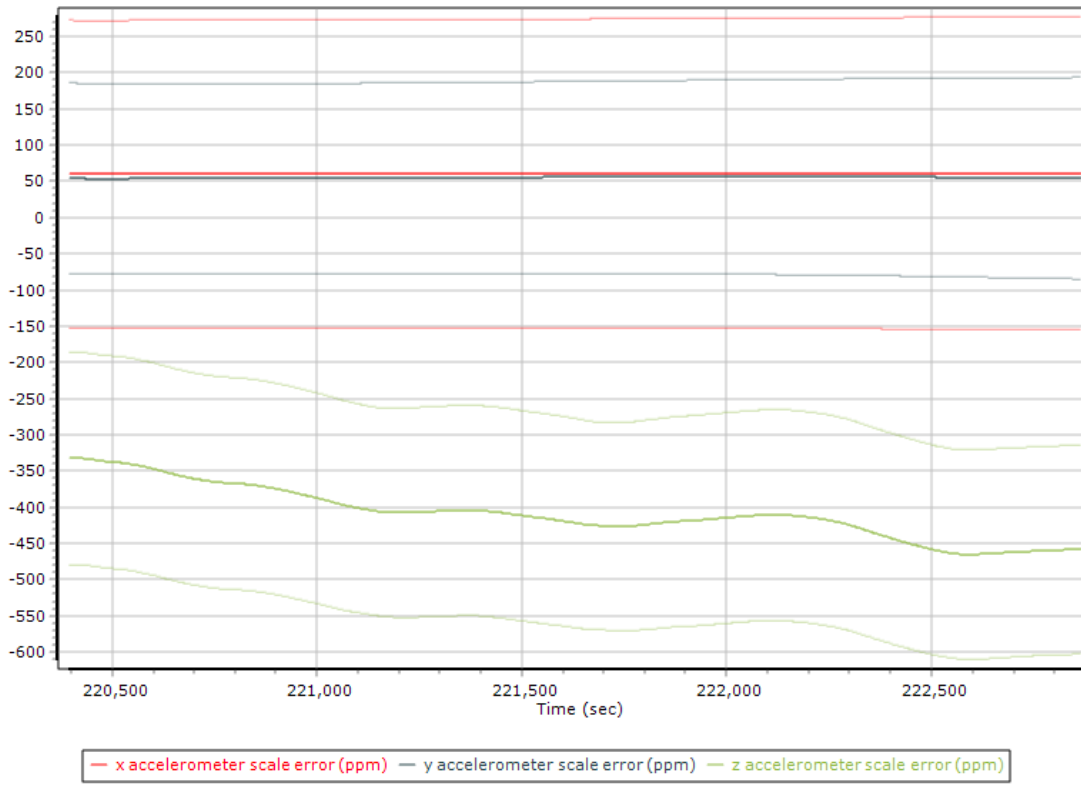
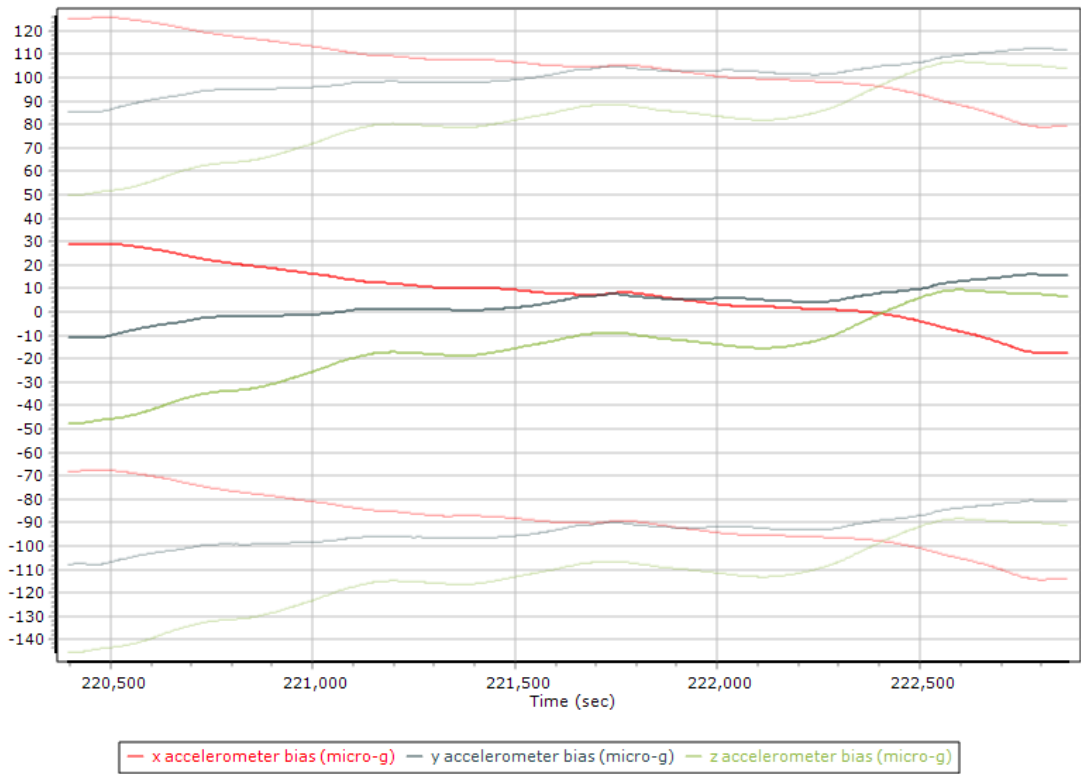


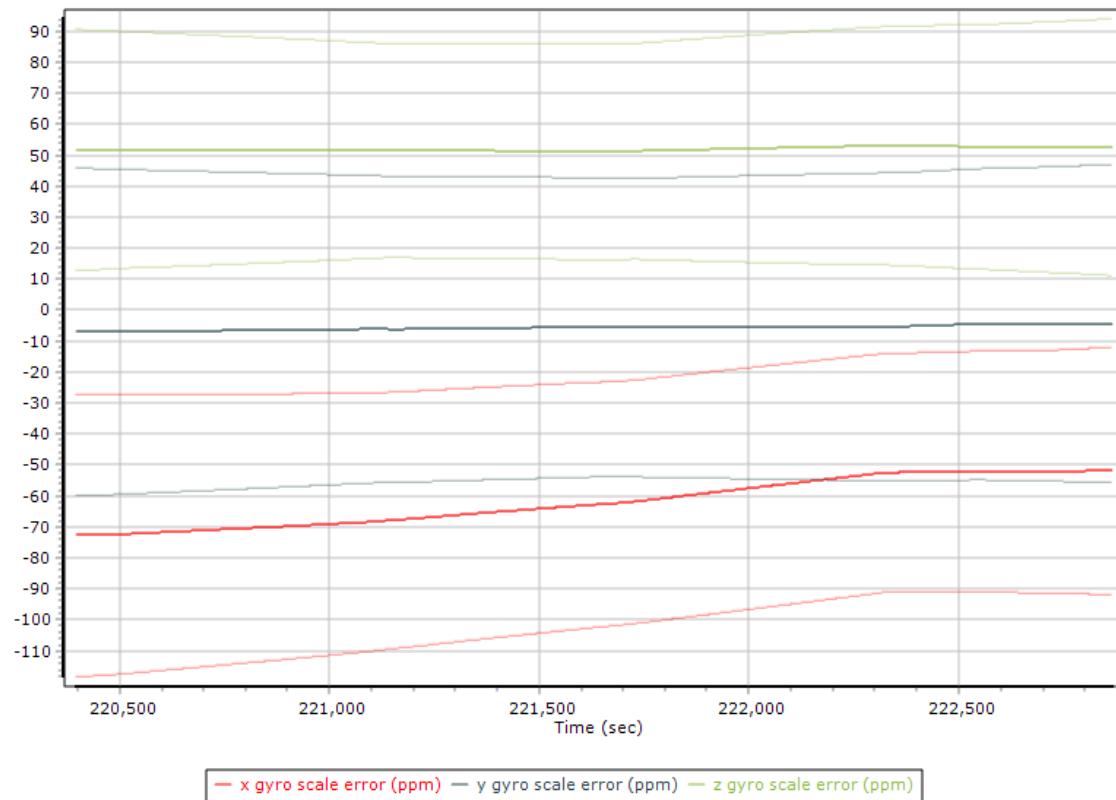
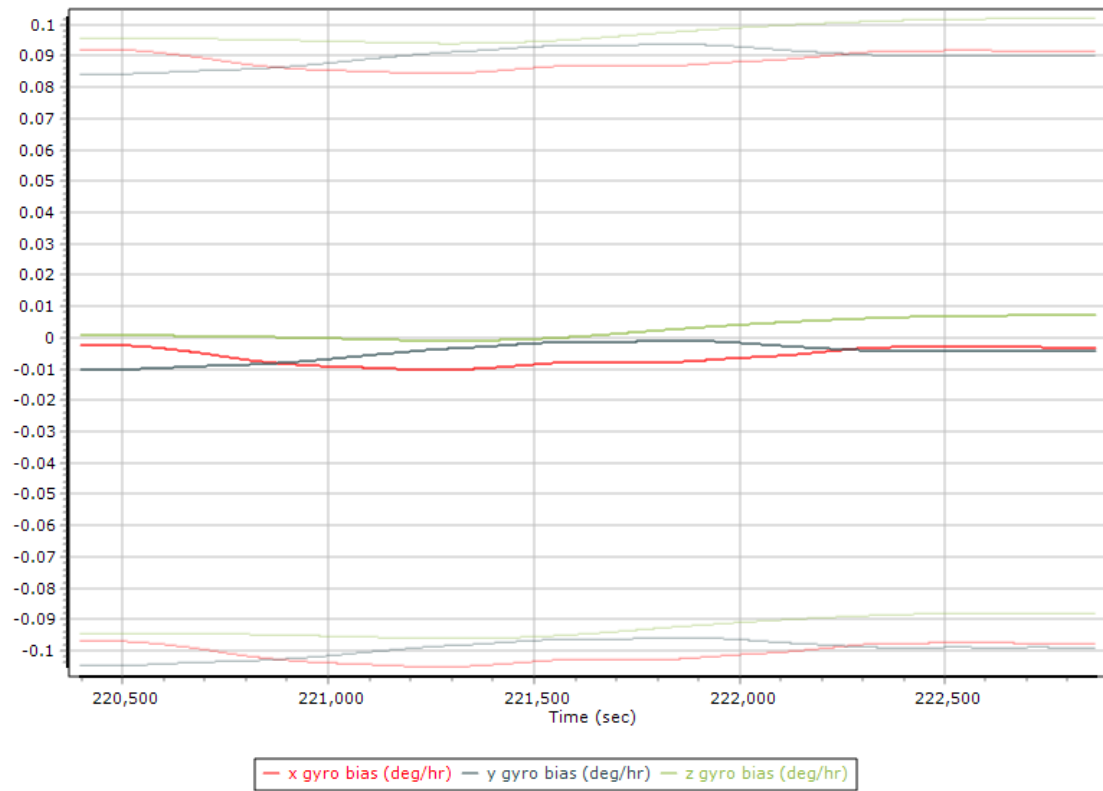


Forward Reverse

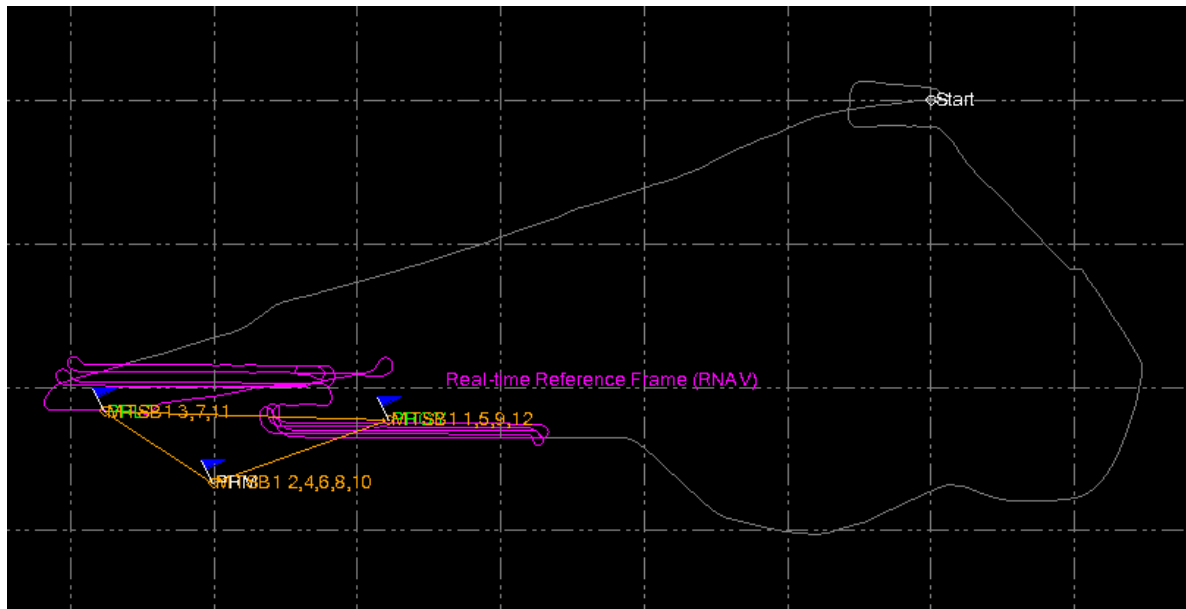
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





AZT18144A



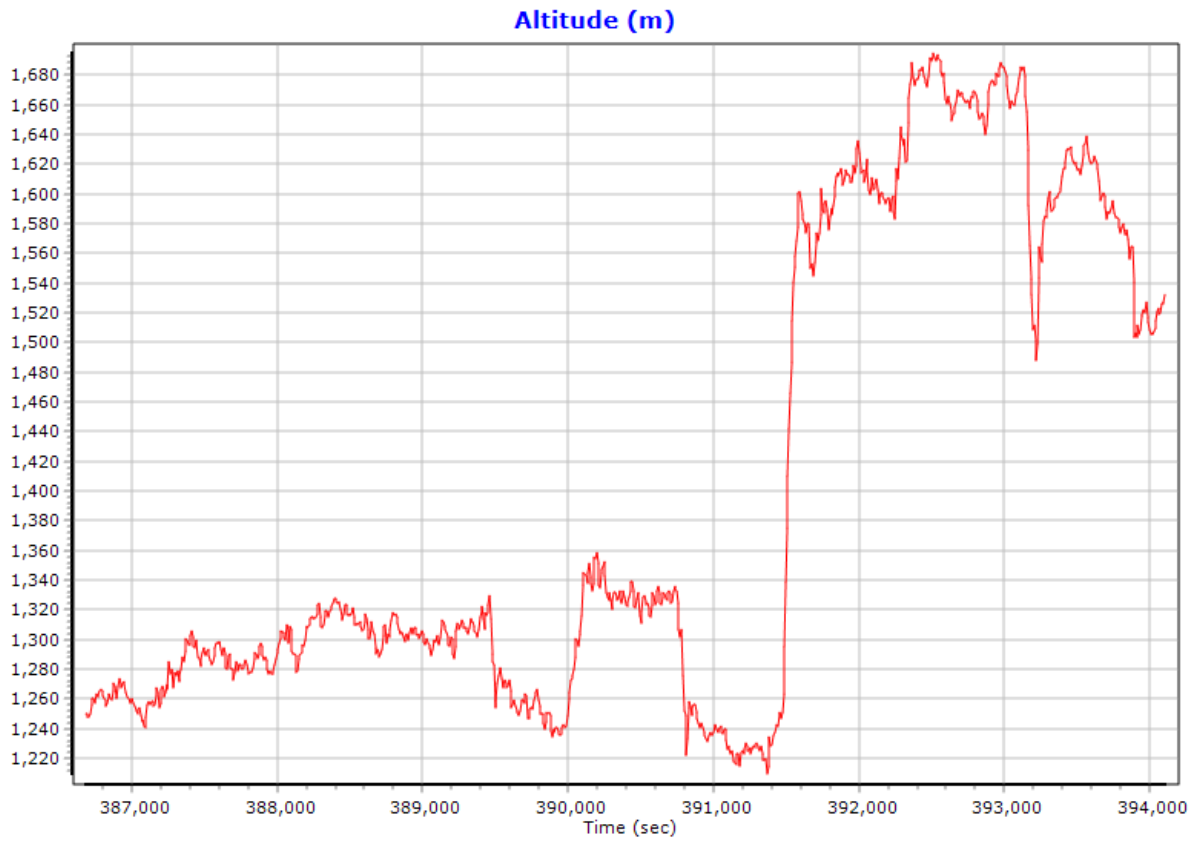
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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		

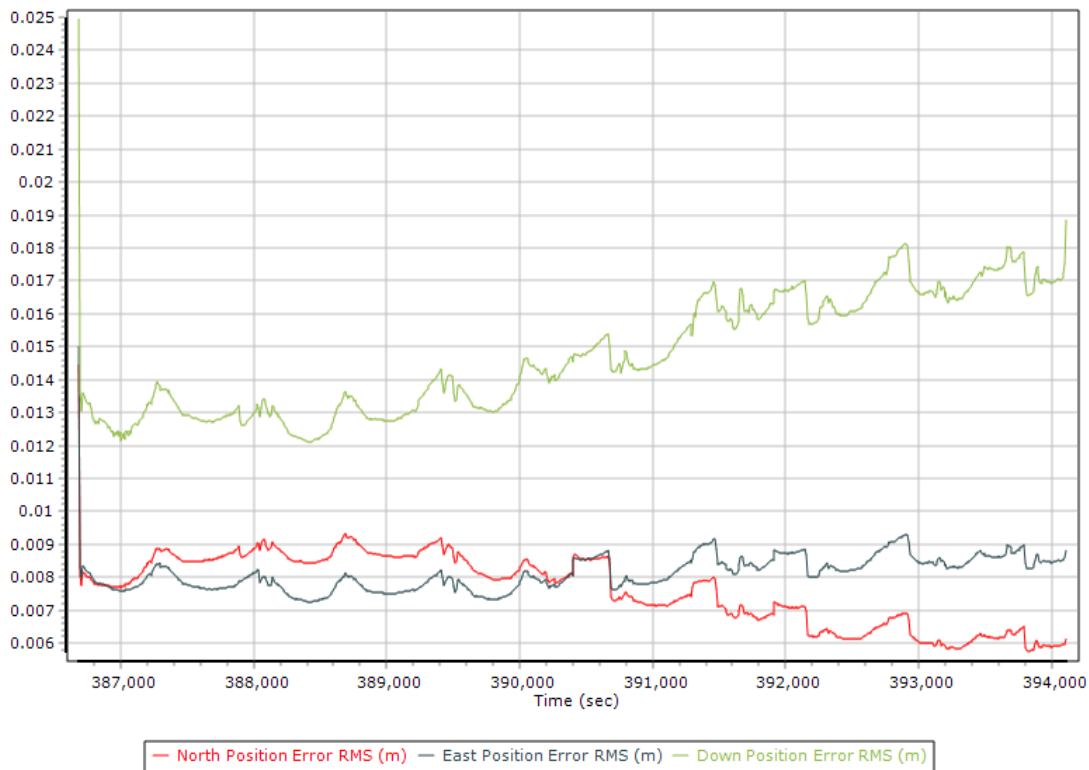
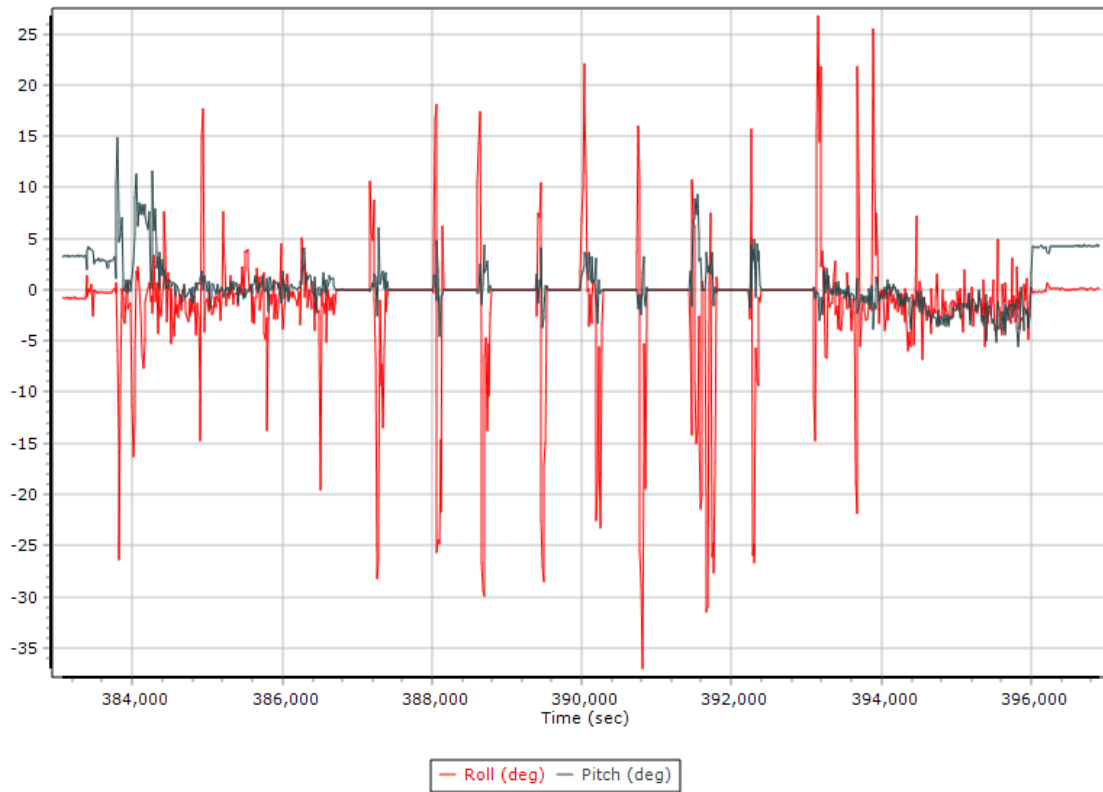
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

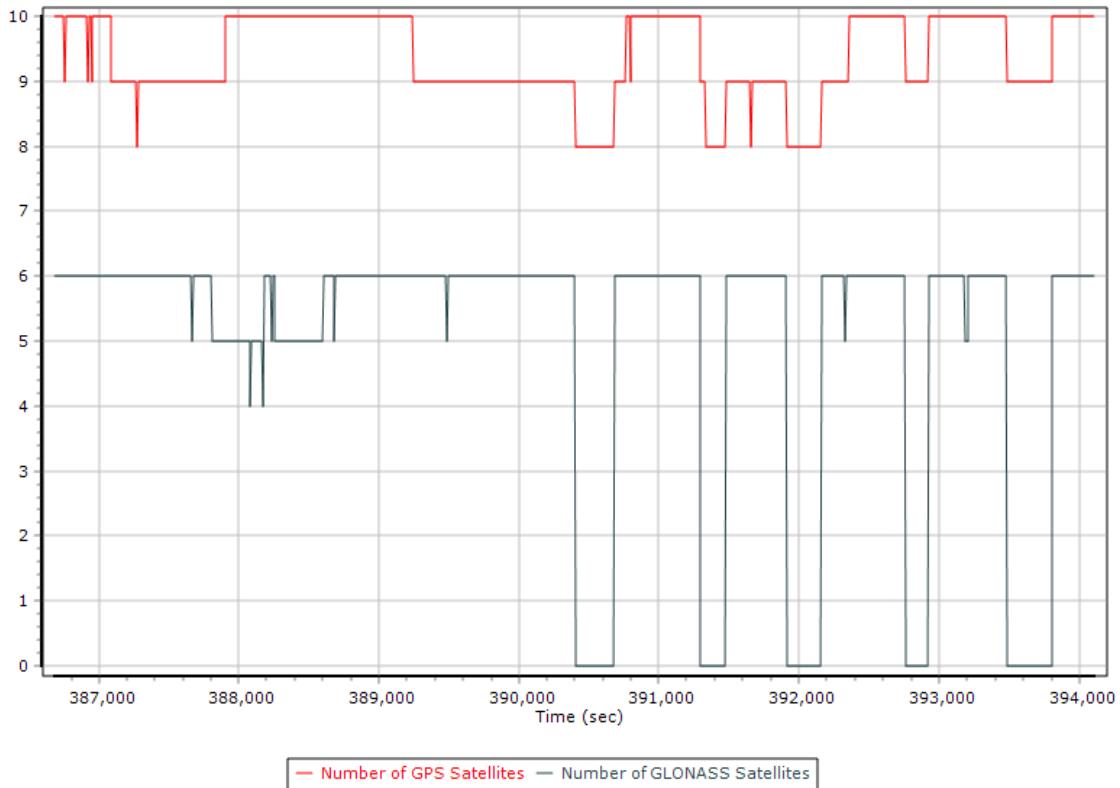
Timing

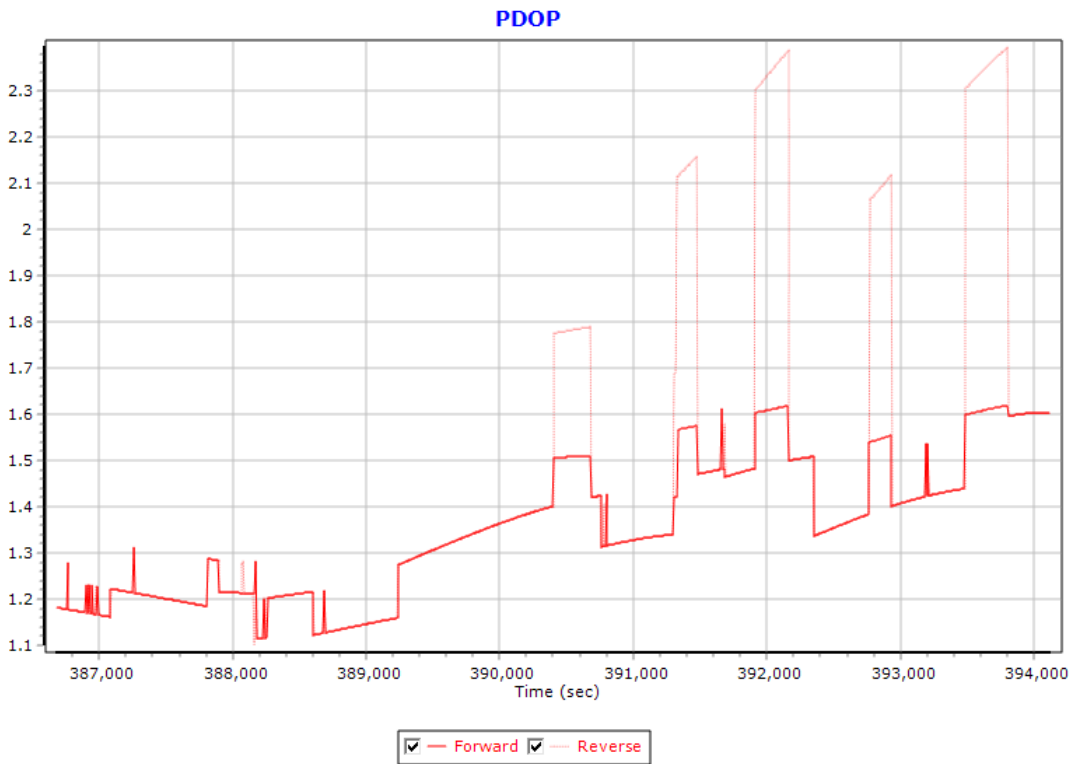
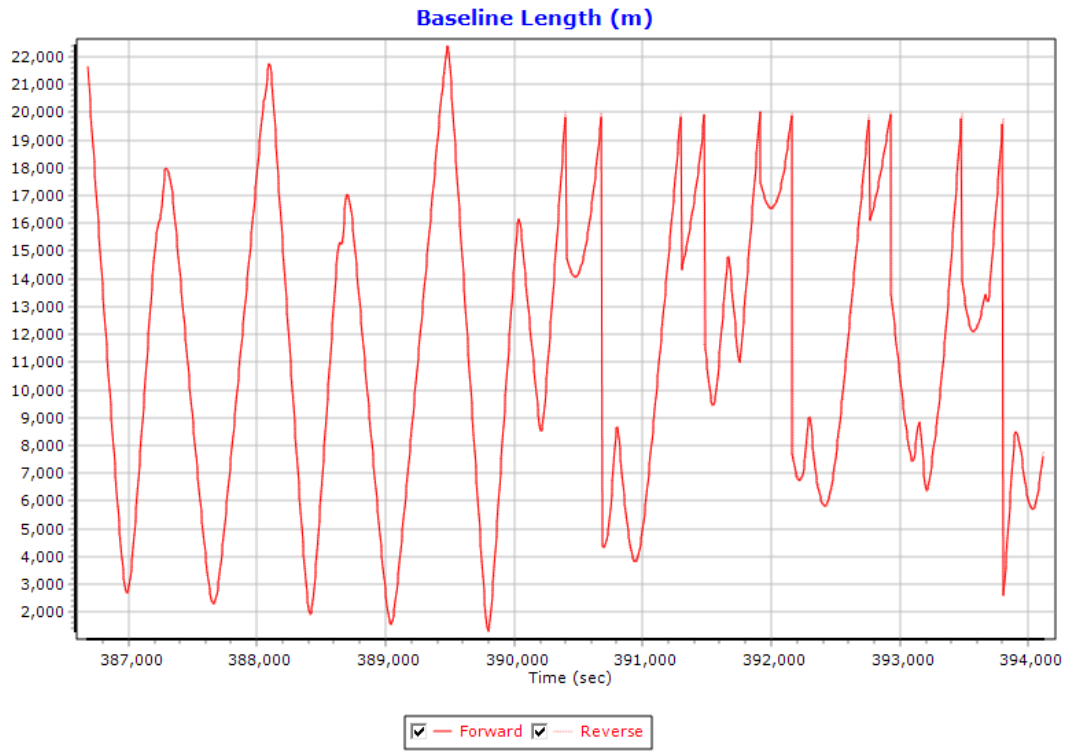
Start	386682.339	Data	Incr. (sec)
End	394115.067	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset: 18.000

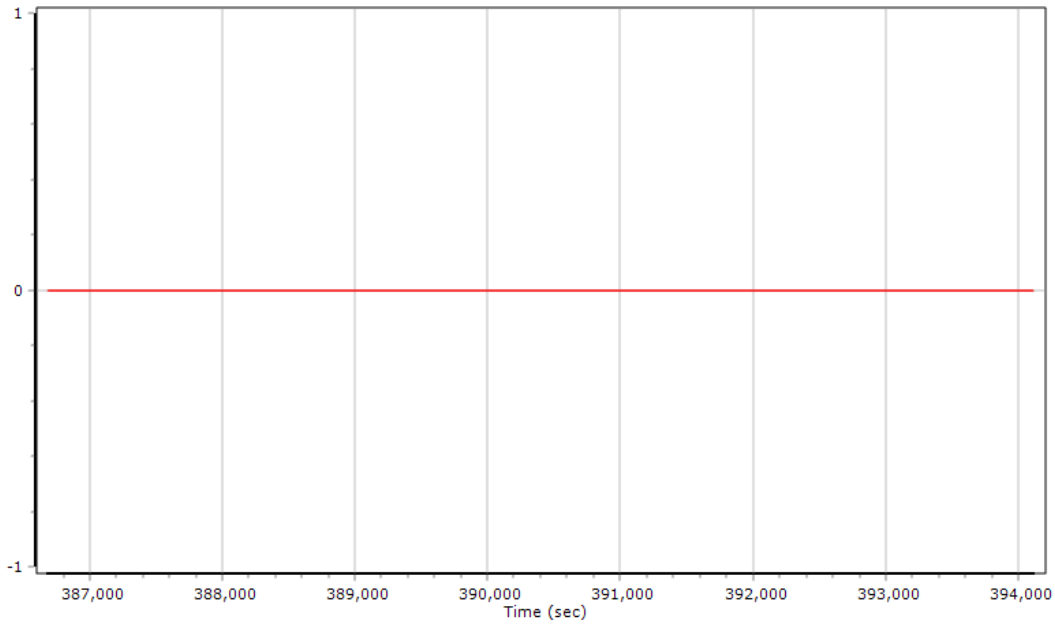








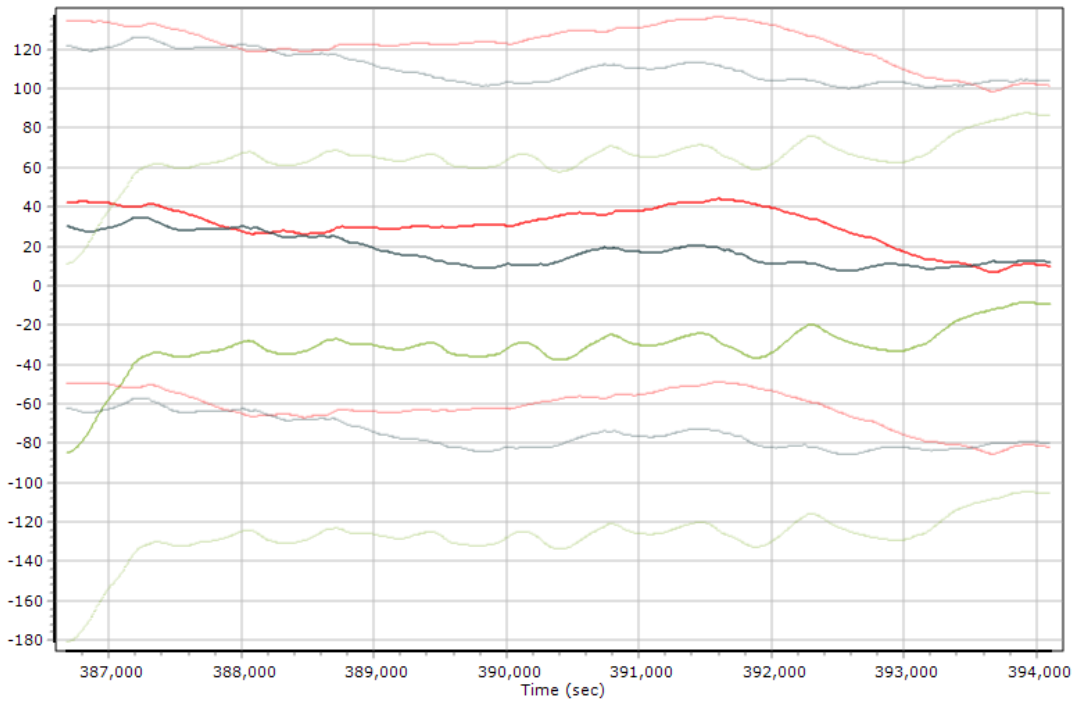
Processing mode



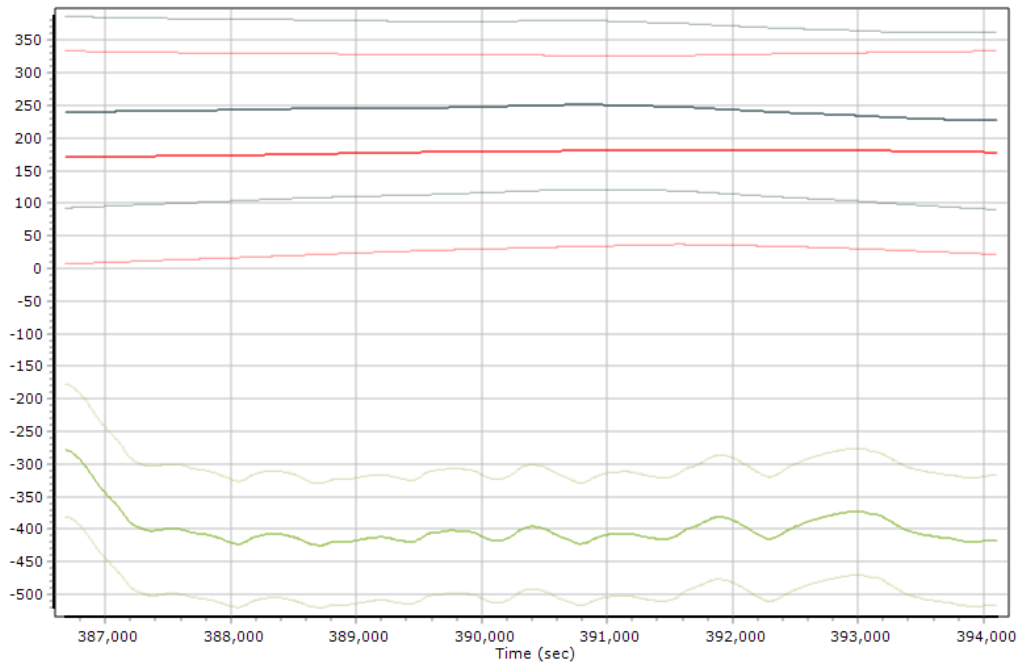
Forward Reverse

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

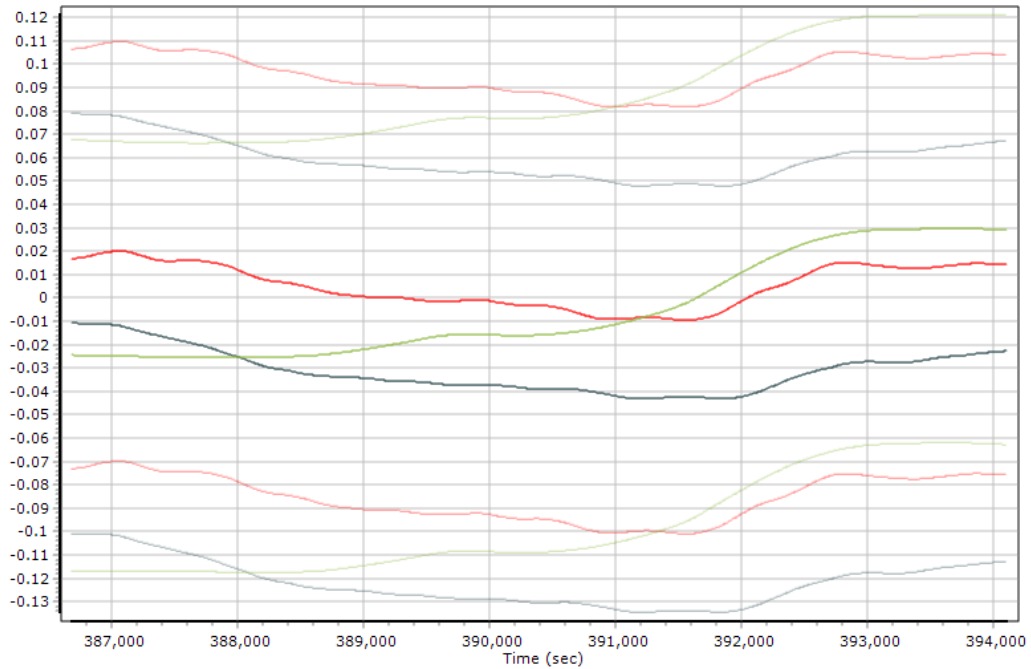
Sensor Errors



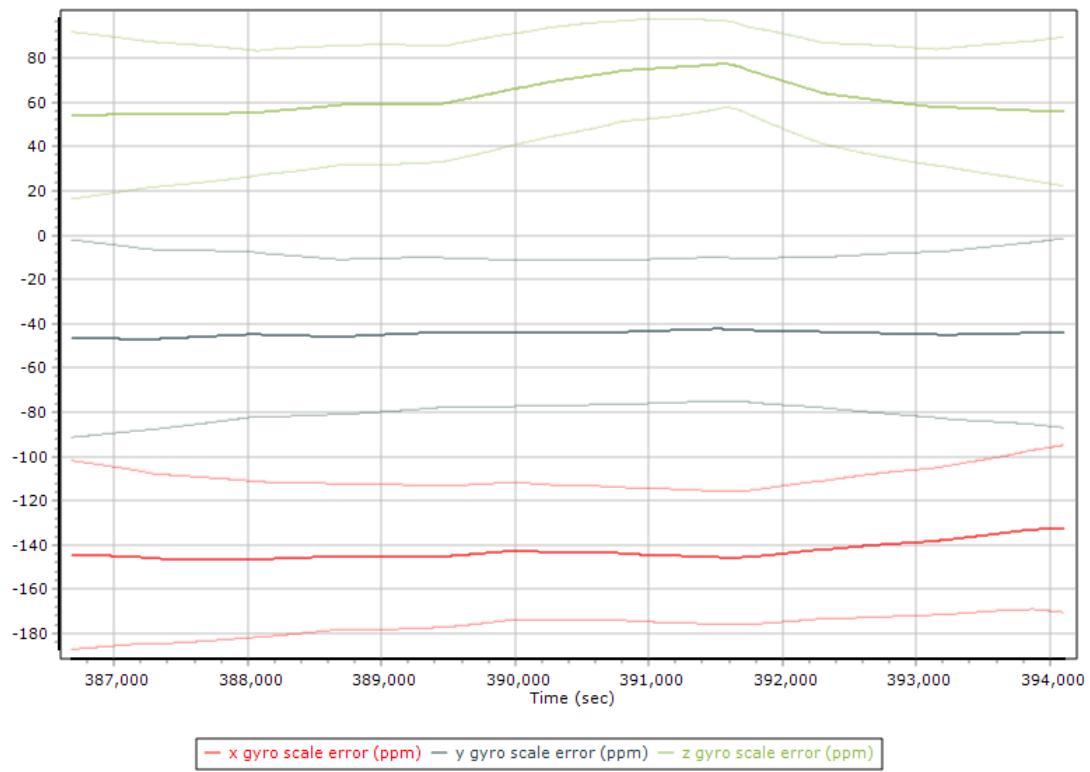
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



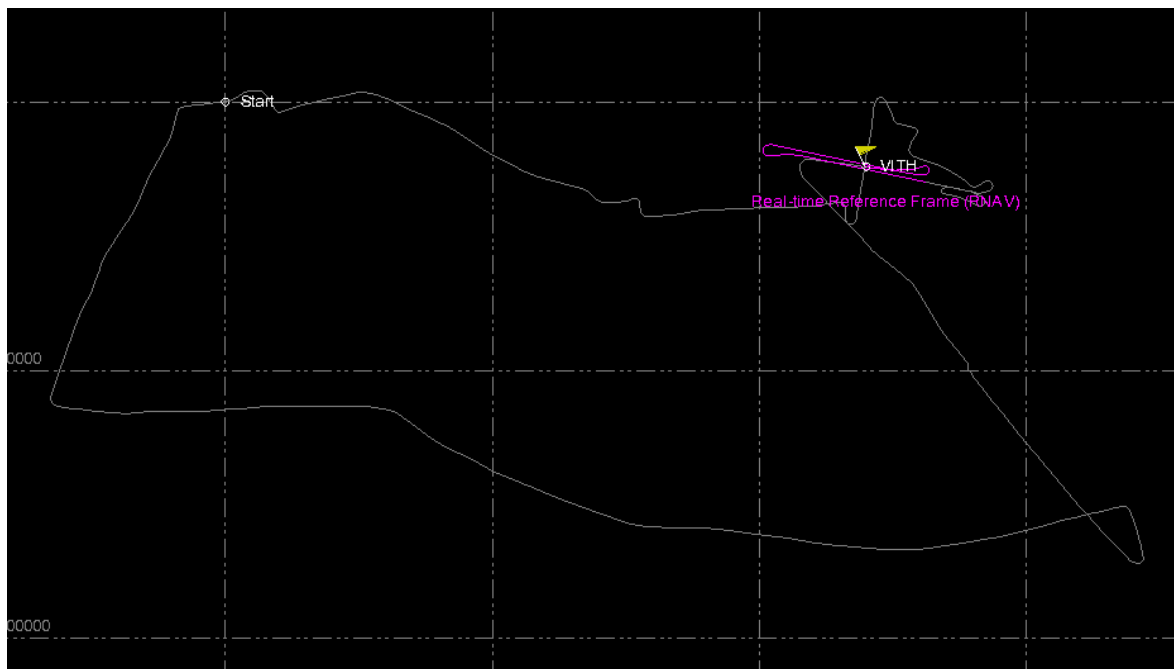
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

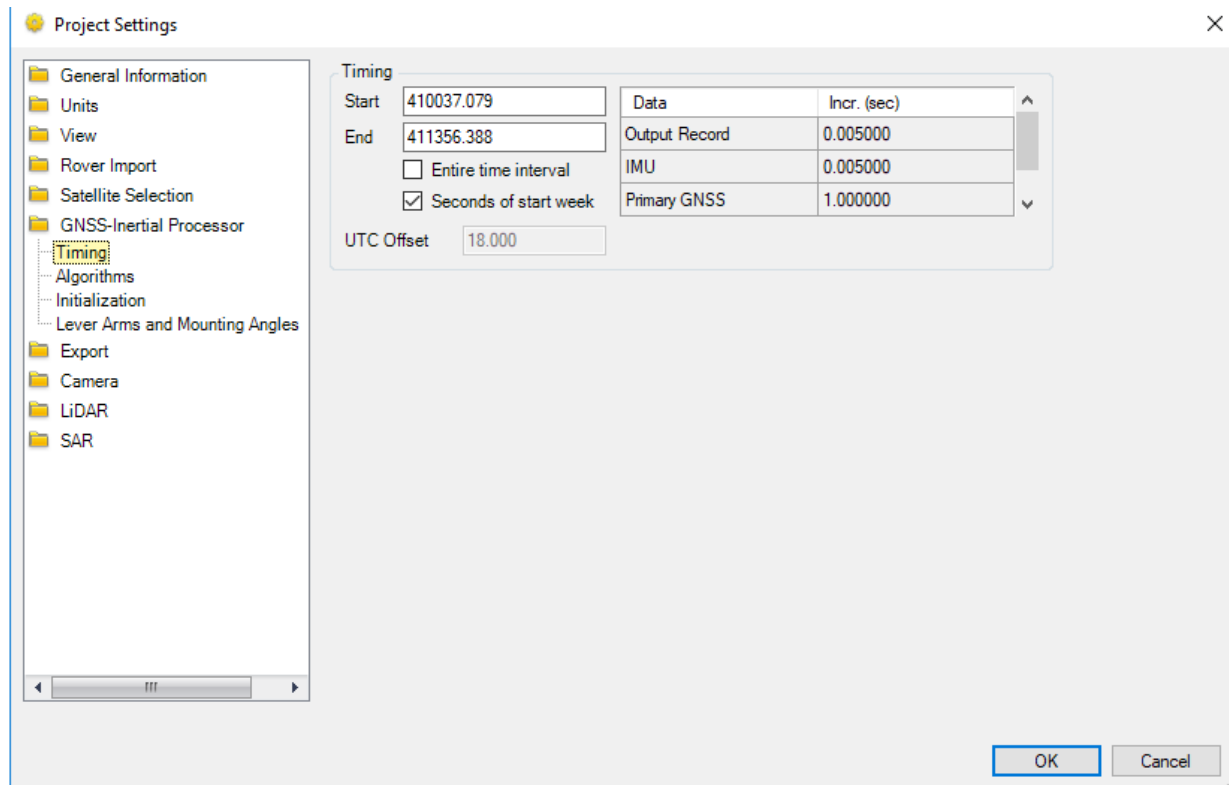
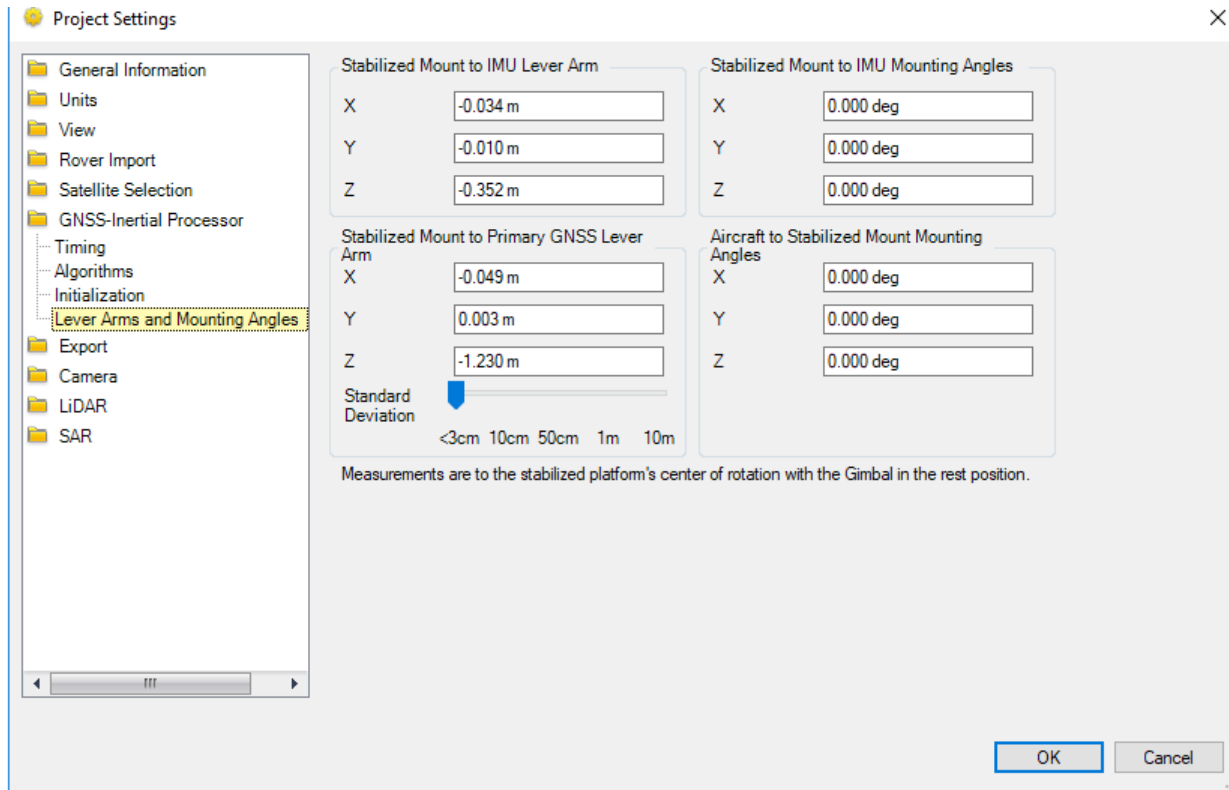


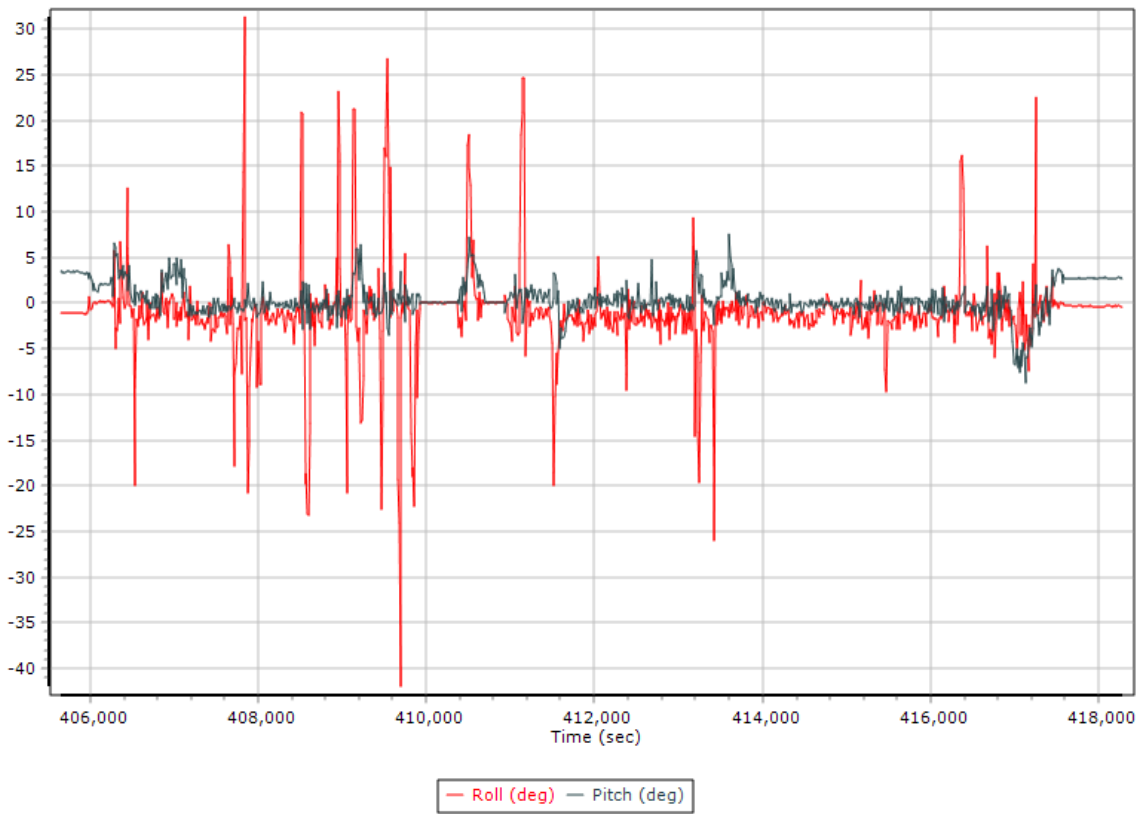
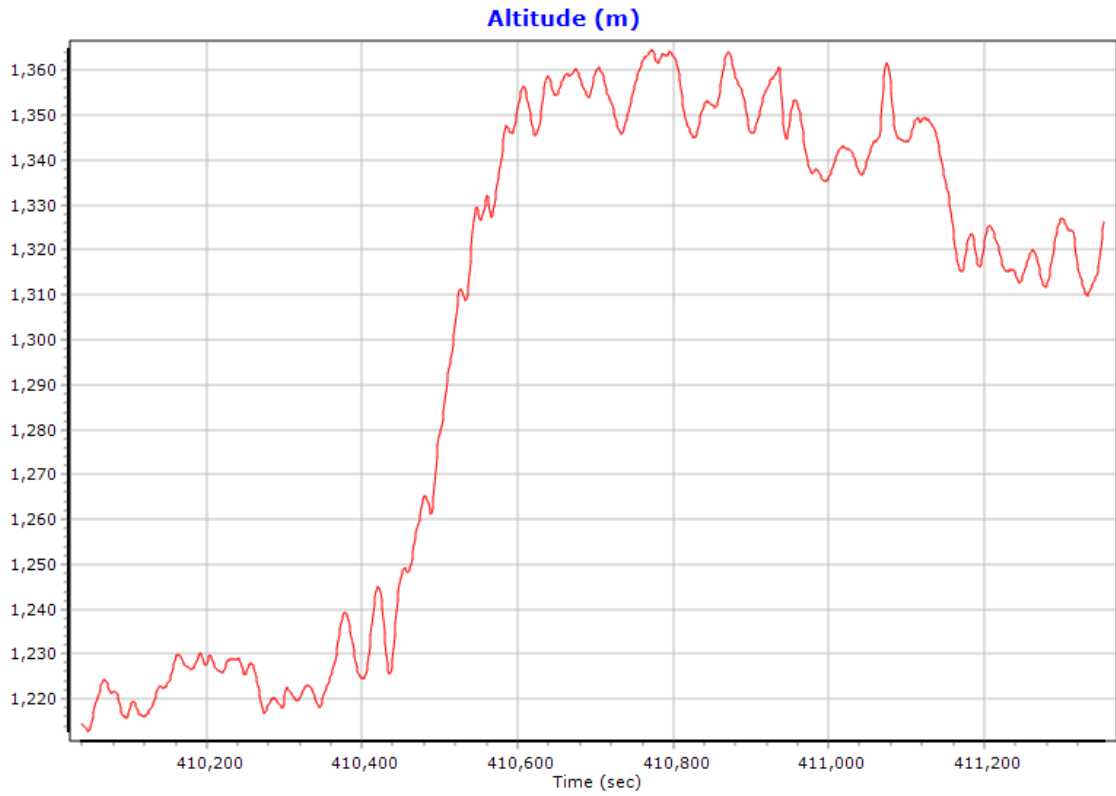
— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

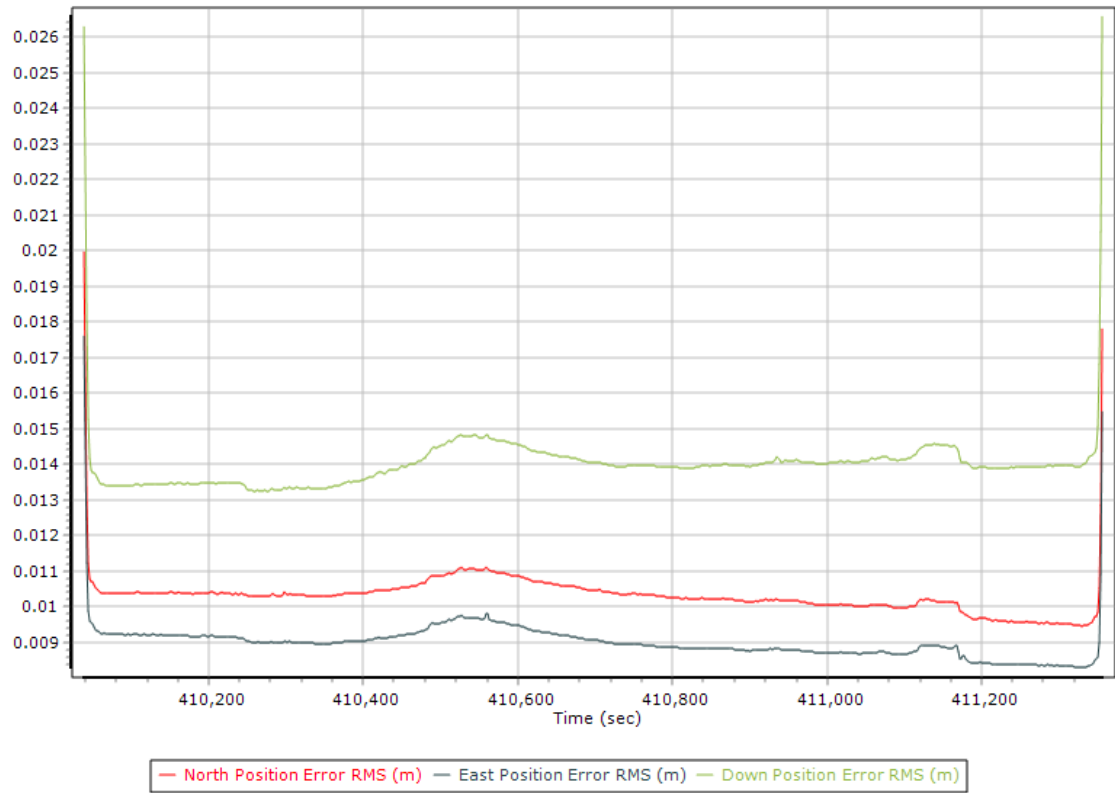


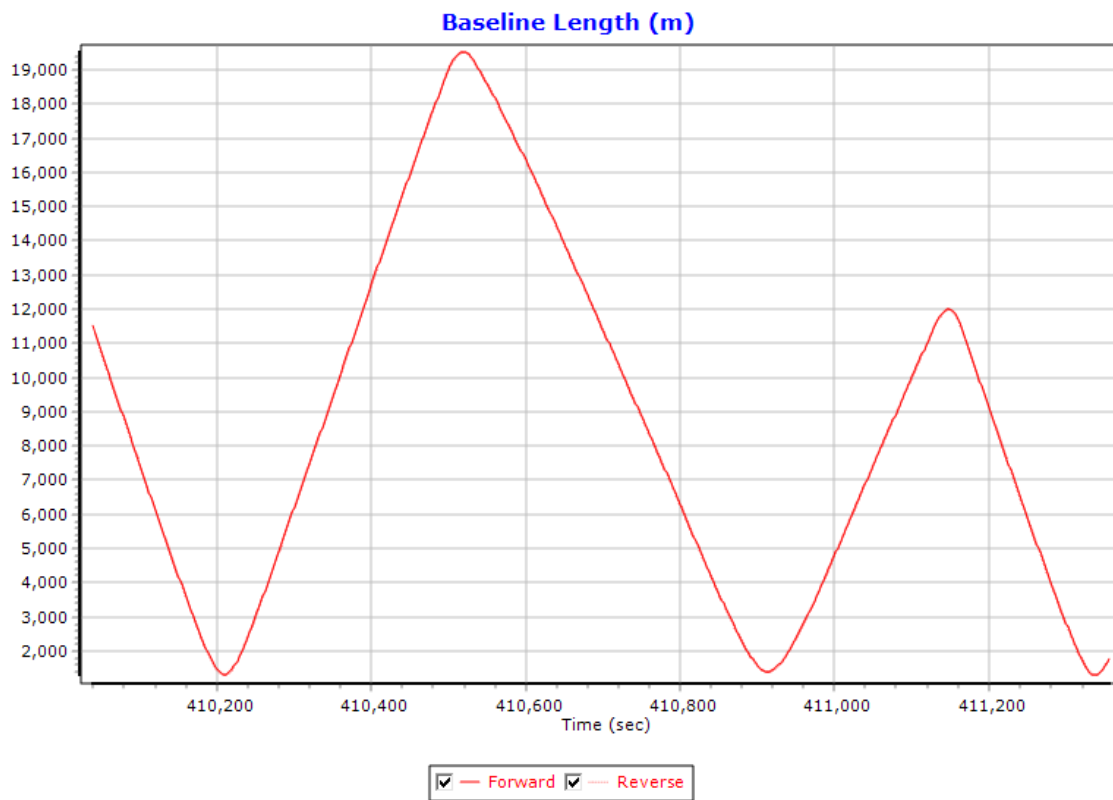
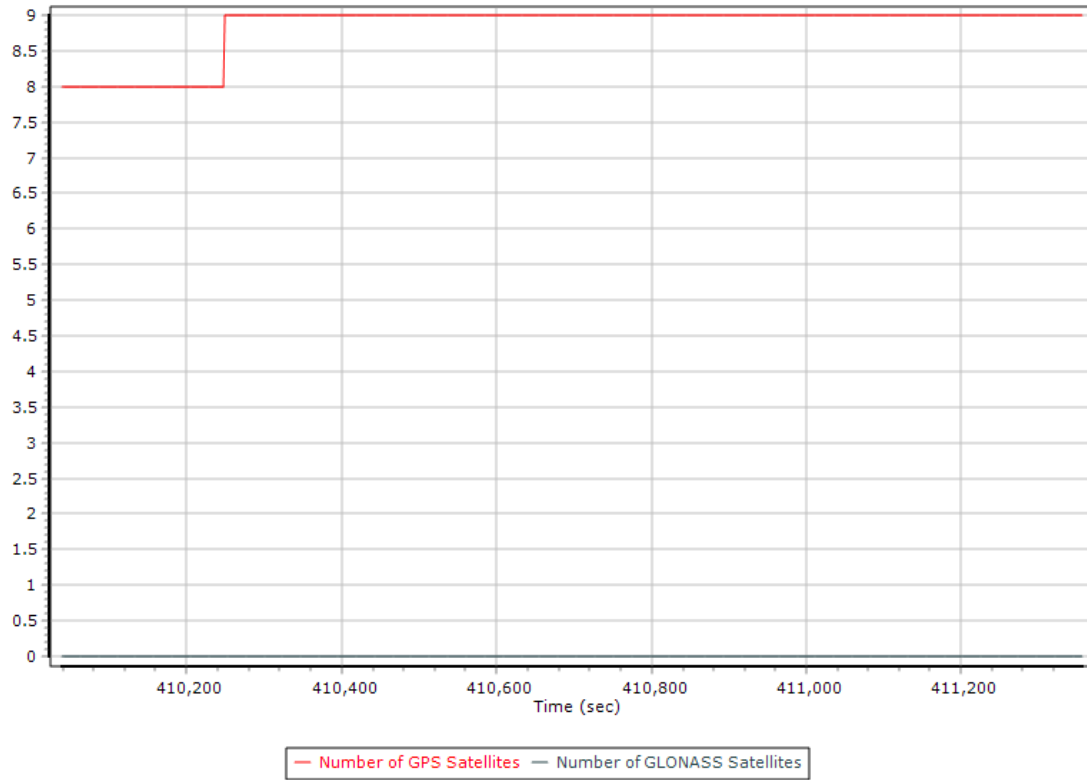
AZT18144B



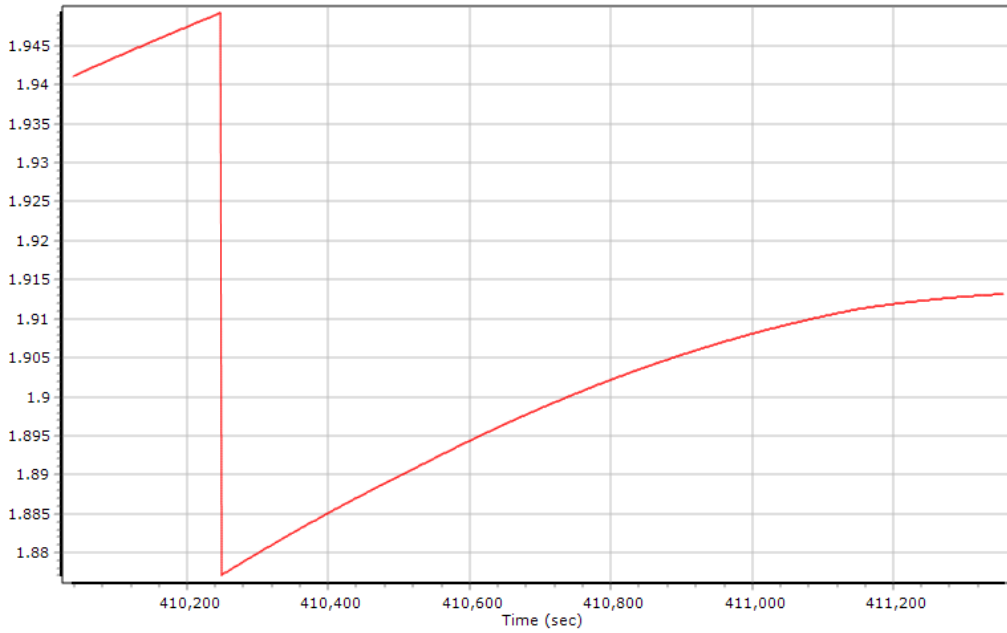






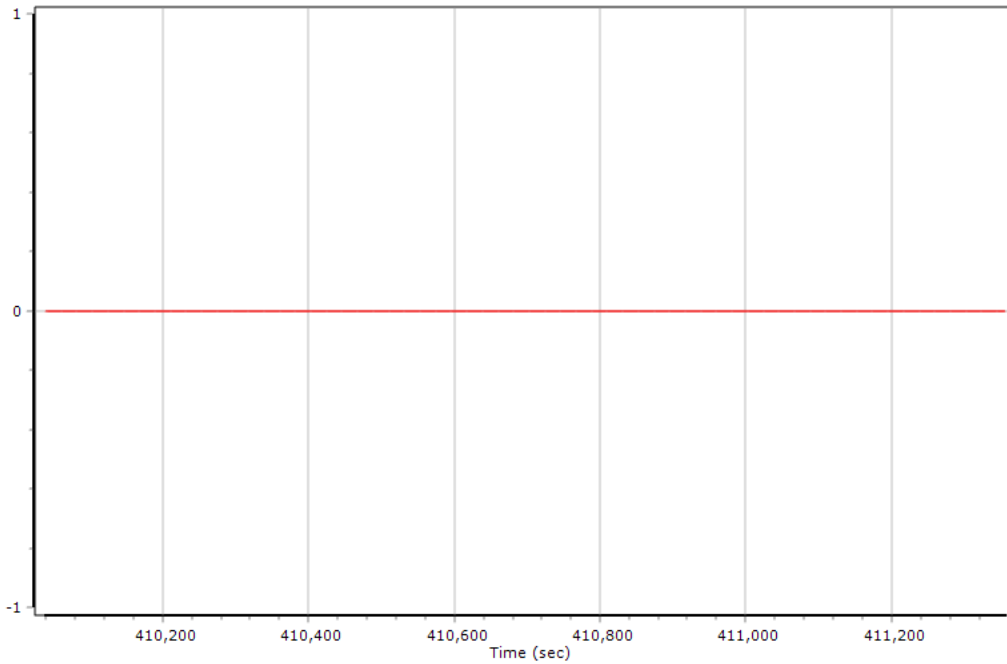


PDOP



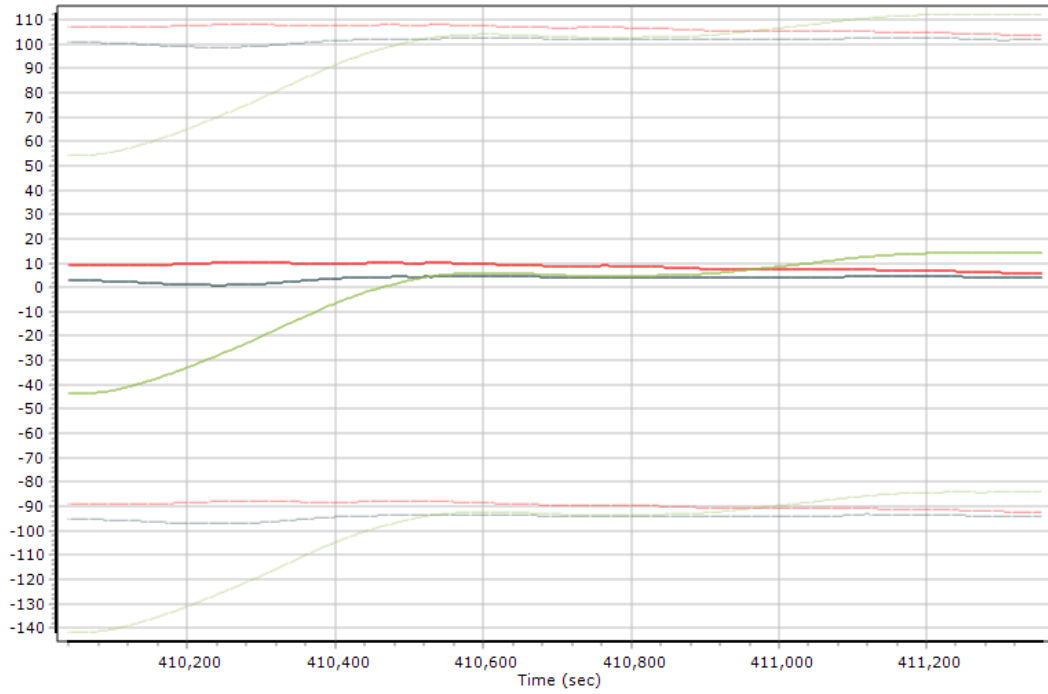
Forward Reverse

Processing mode

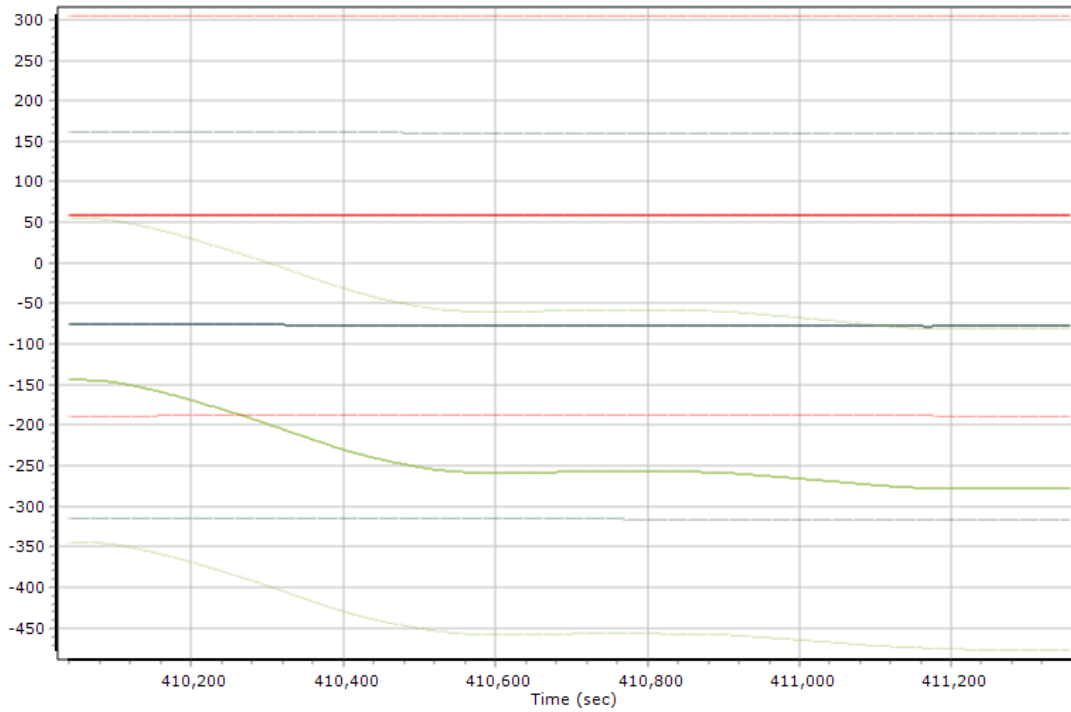


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

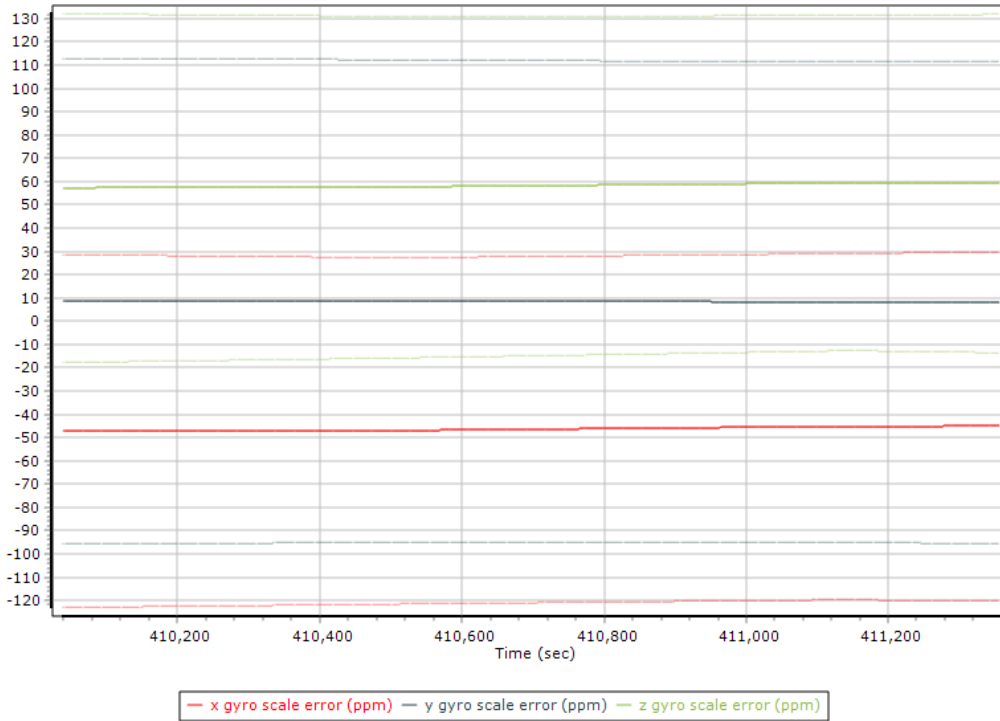
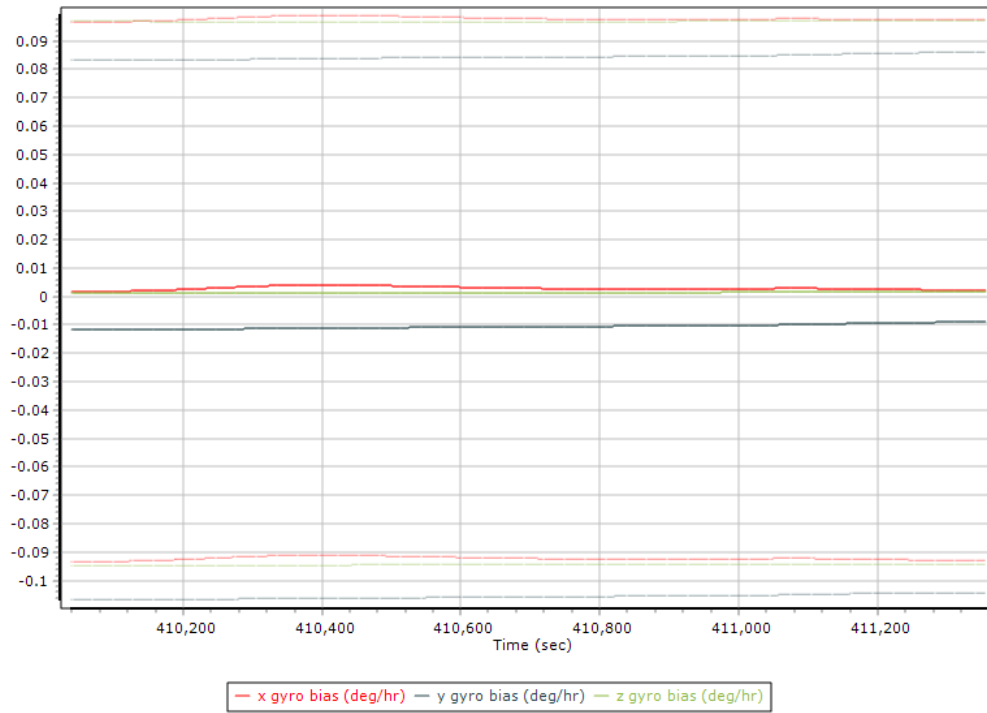
Sensor Errors



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



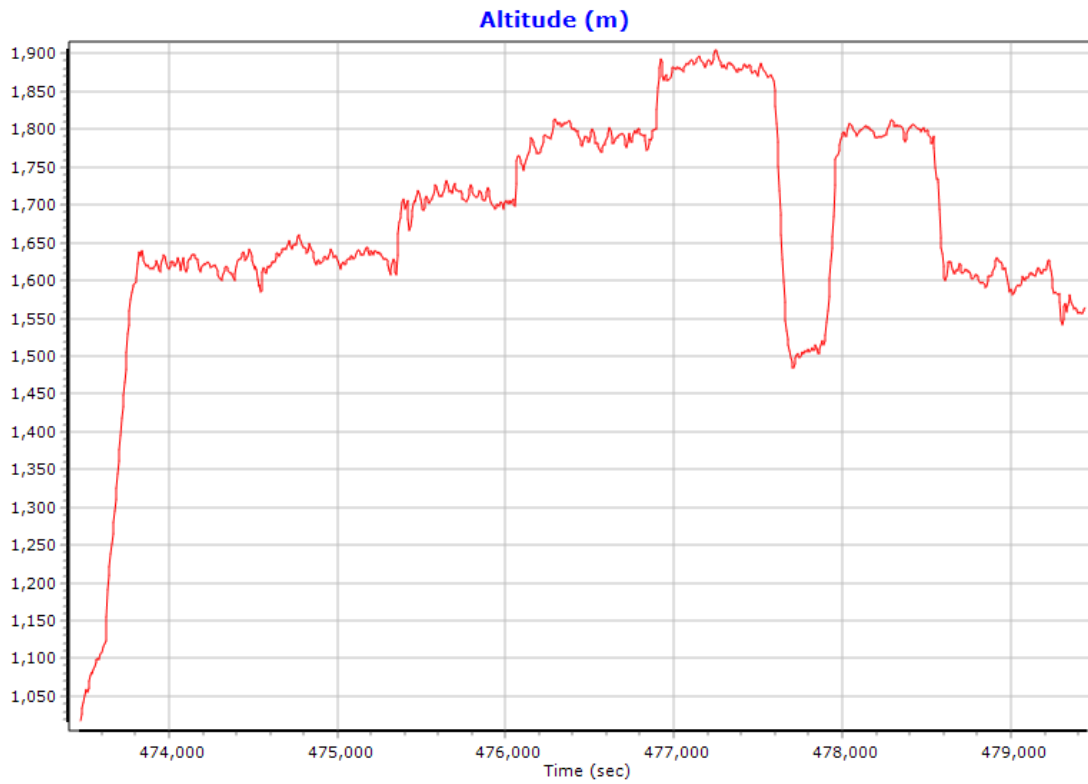
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

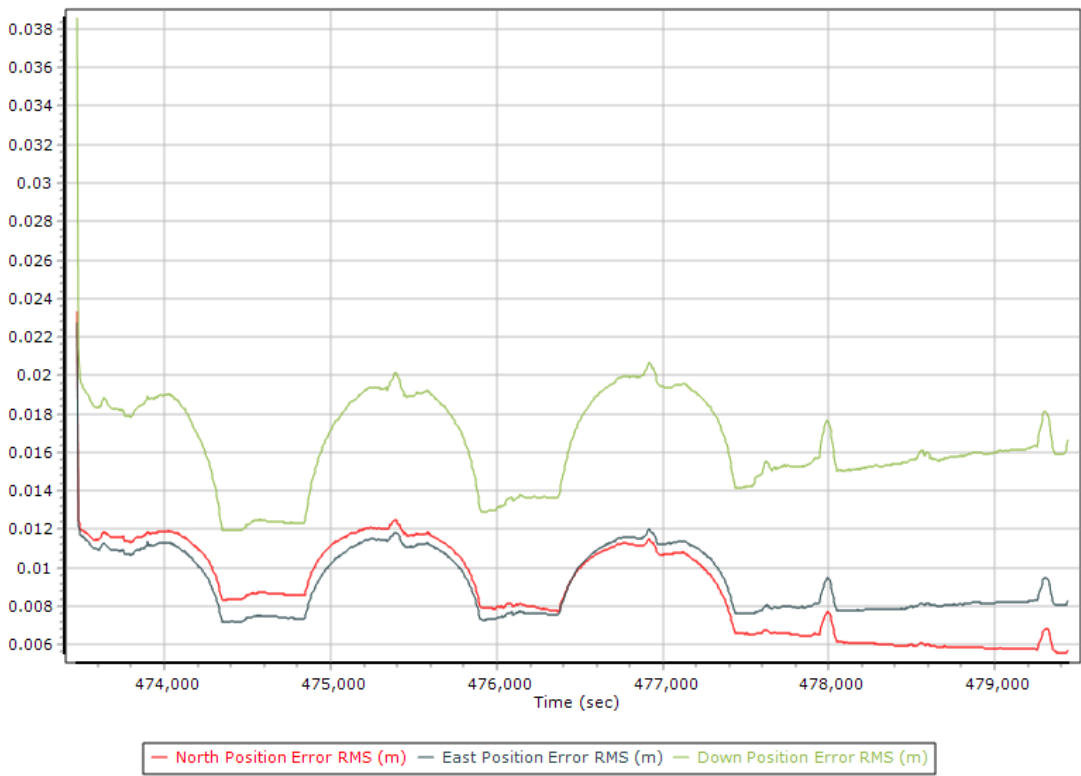


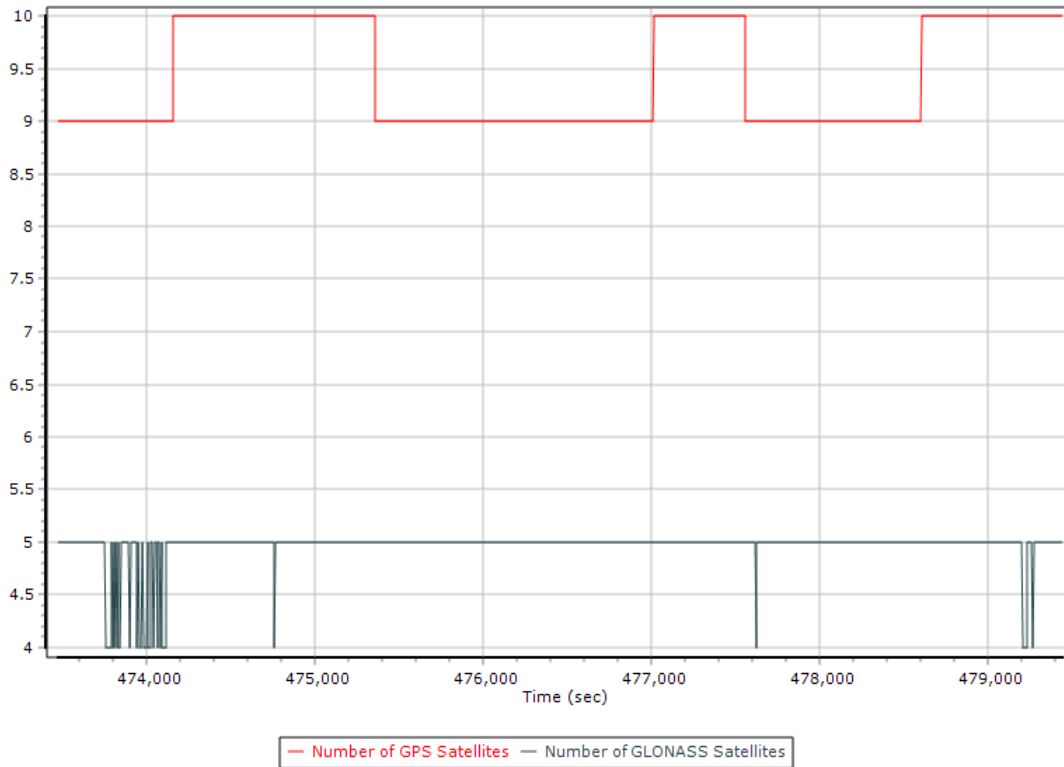
Timing

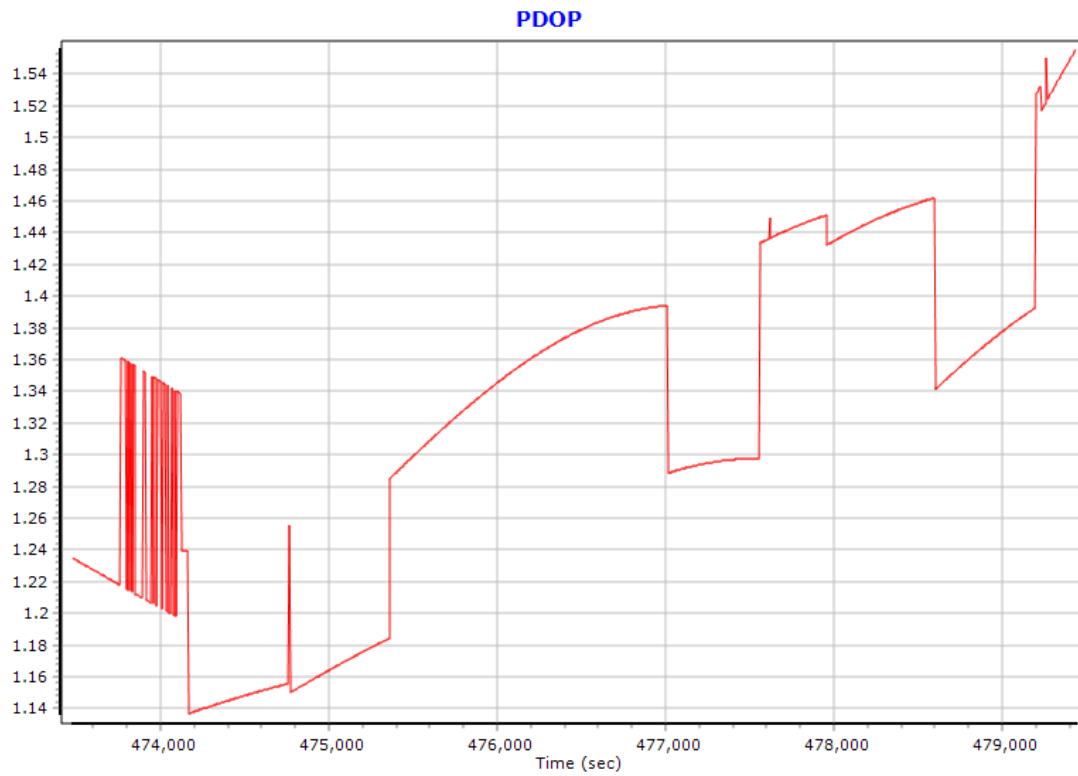
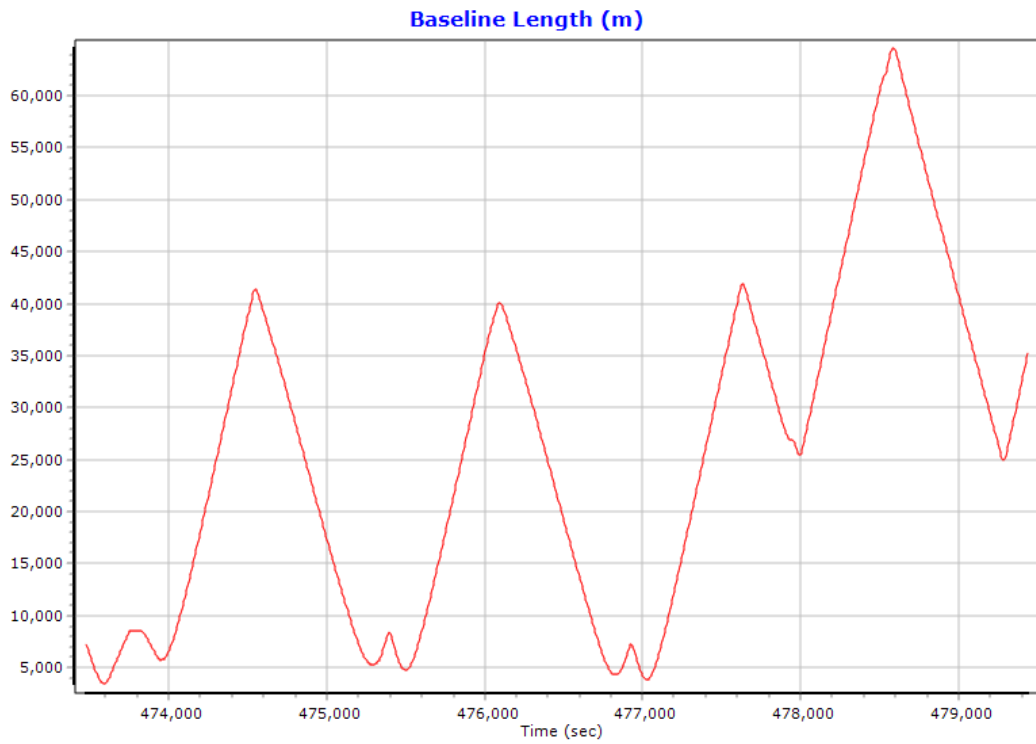
Start	473475.931	Data	Incr. (sec)
End	479445.000	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset 18.000

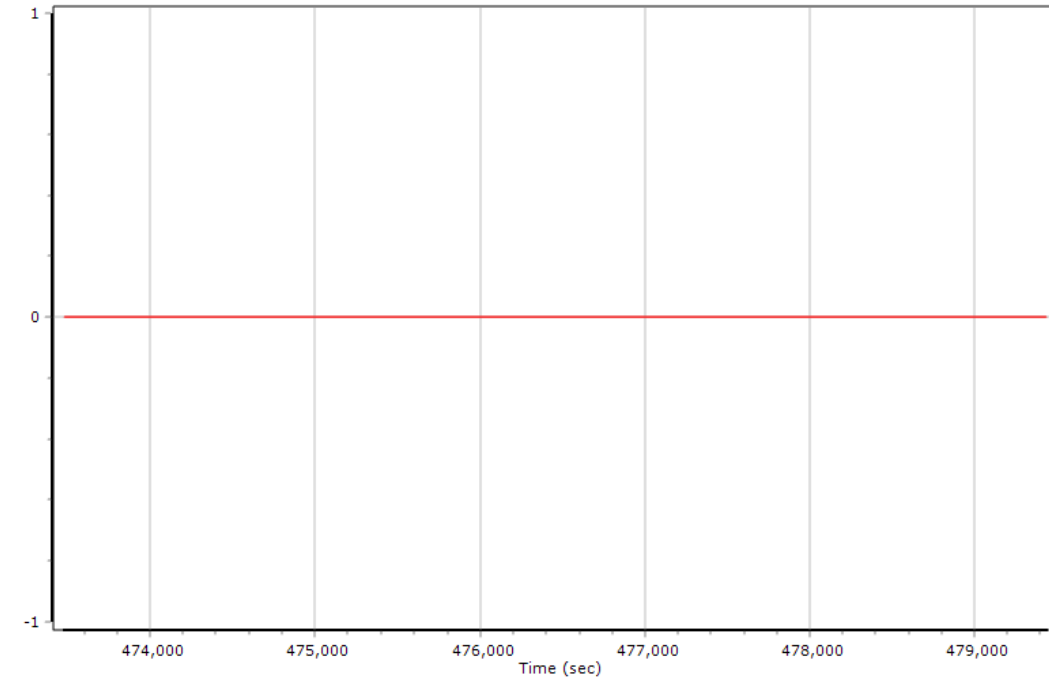






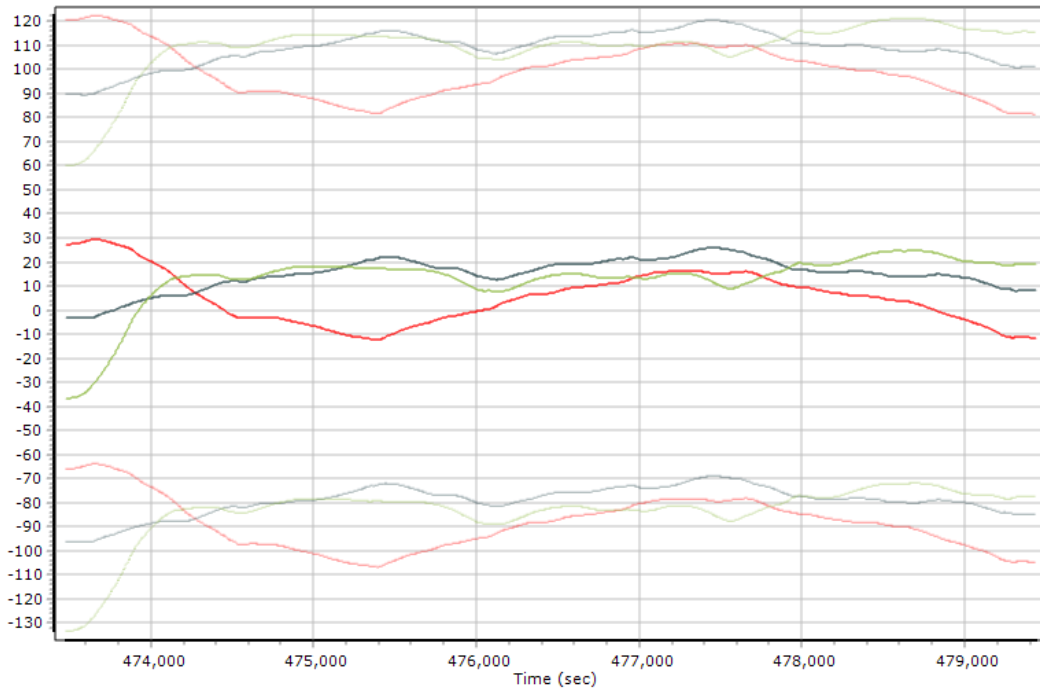


Processing mode

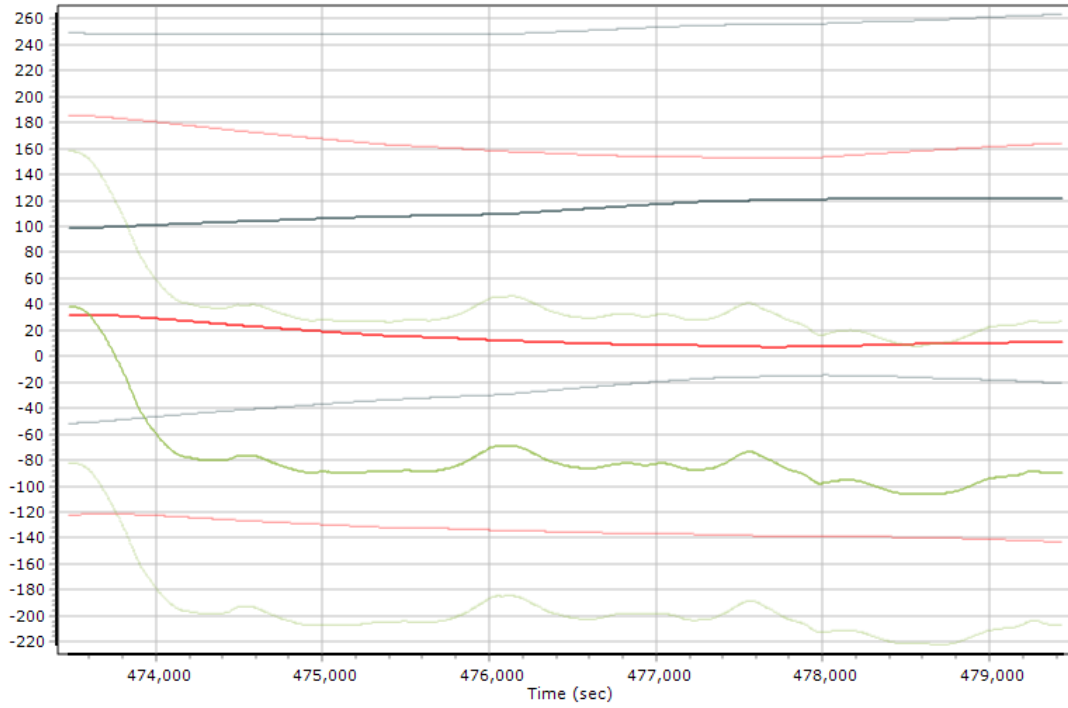


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

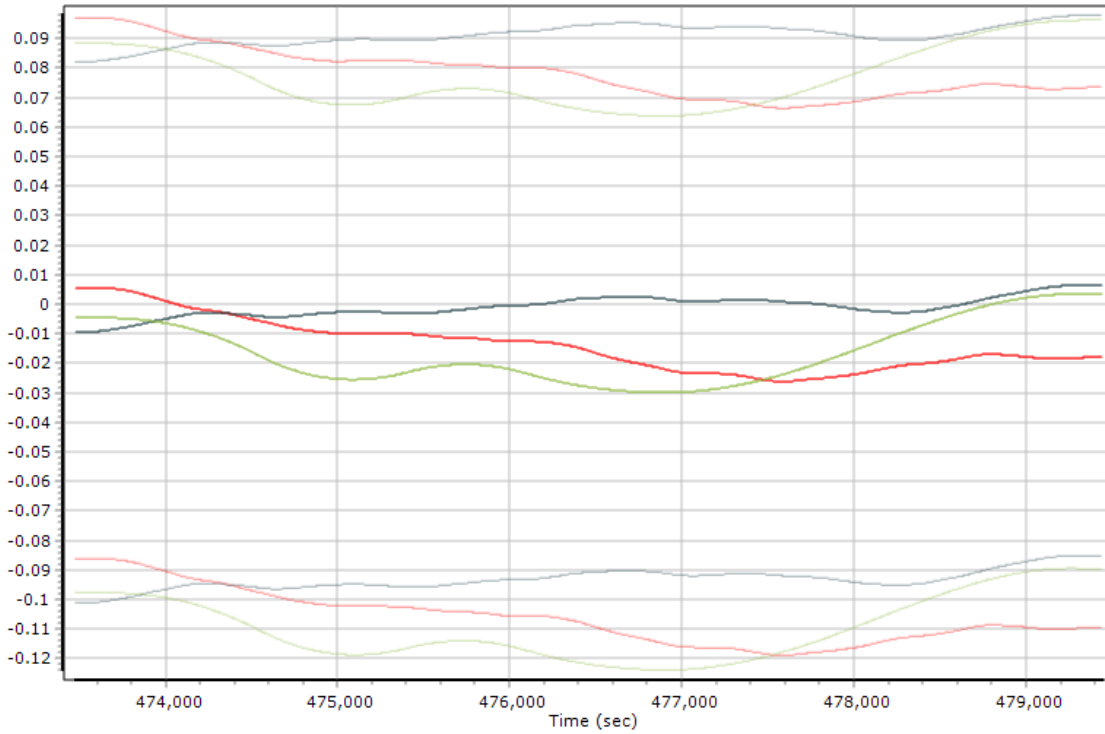
Sensor Error



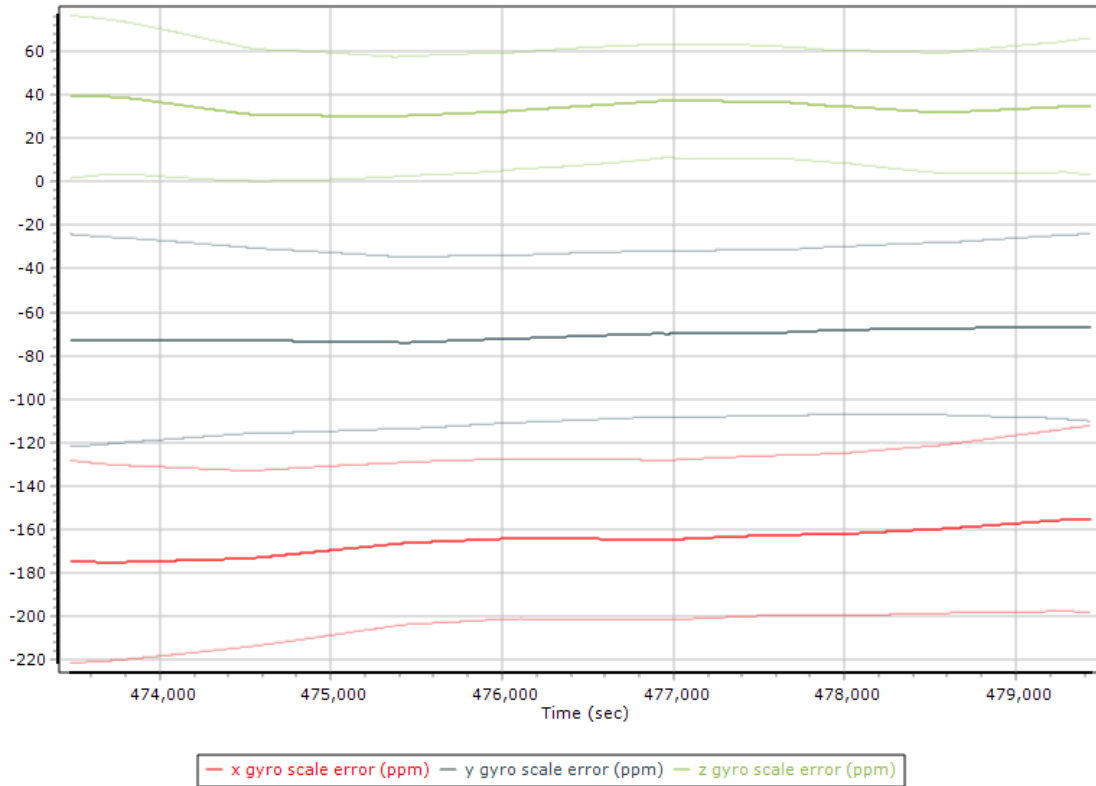
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



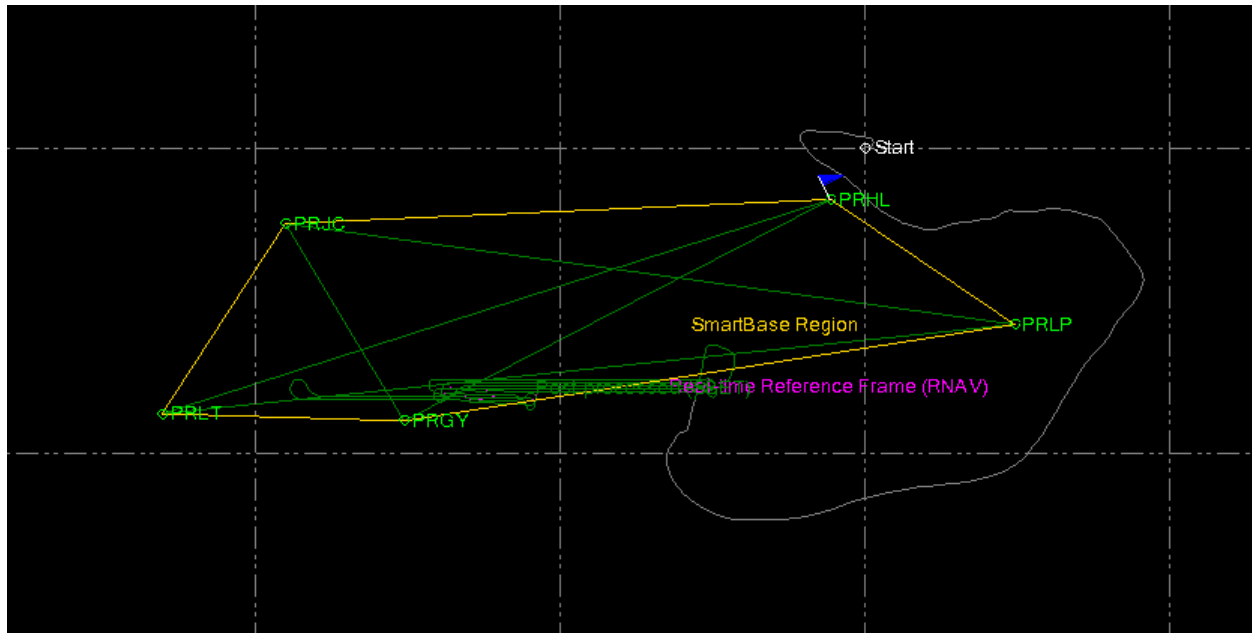
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



AZT18145A



Stabilized Mount to IMU Lever Arm

X	-0.034 m
Y	-0.010 m
Z	-0.352 m

Stabilized Mount to IMU Mounting Angles

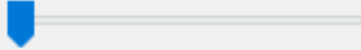
X	0.000 deg
Y	0.000 deg
Z	0.000 deg

Stabilized Mount to Primary GNSS Lever Arm

X	-0.049 m
Y	0.003 m
Z	-0.738 m

Aircraft to Stabilized Mount Mounting Angles

X	0.000 deg
Y	0.000 deg
Z	0.000 deg

Standard Deviation 

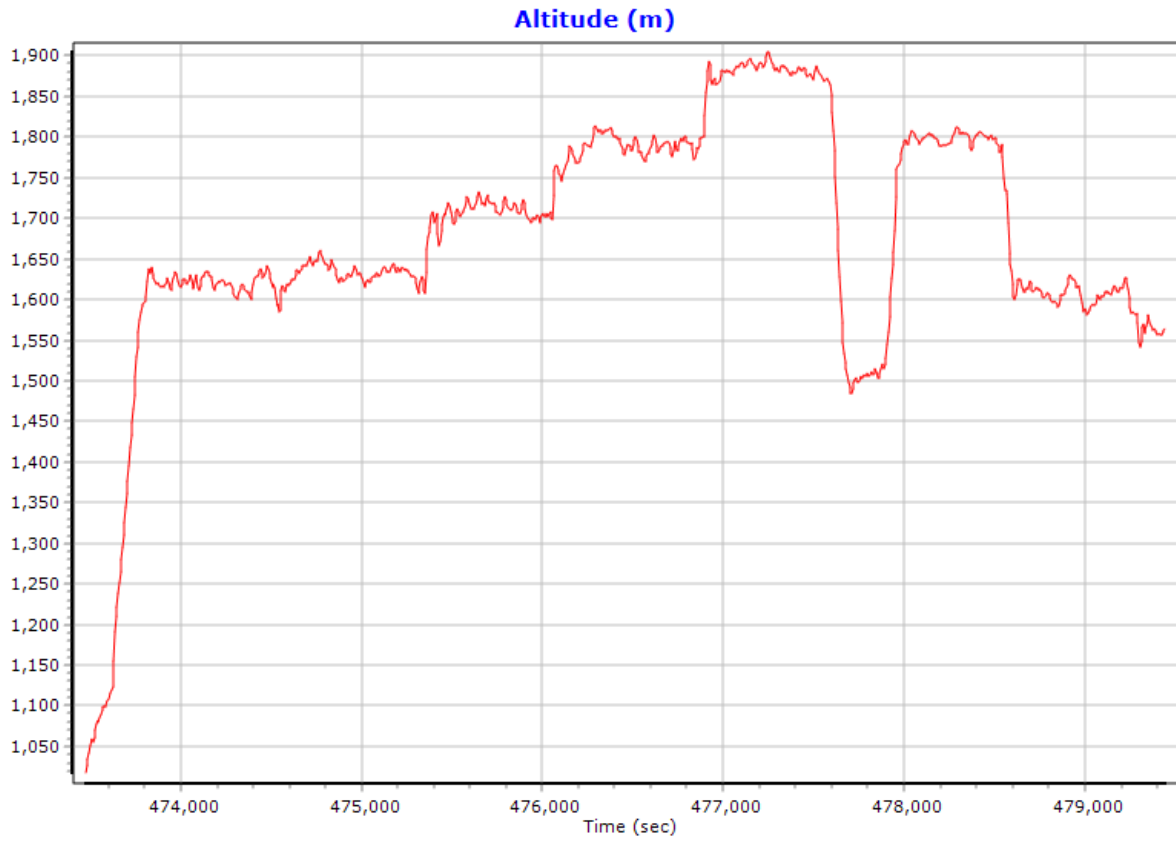
<3cm 10cm 50cm 1m 10m

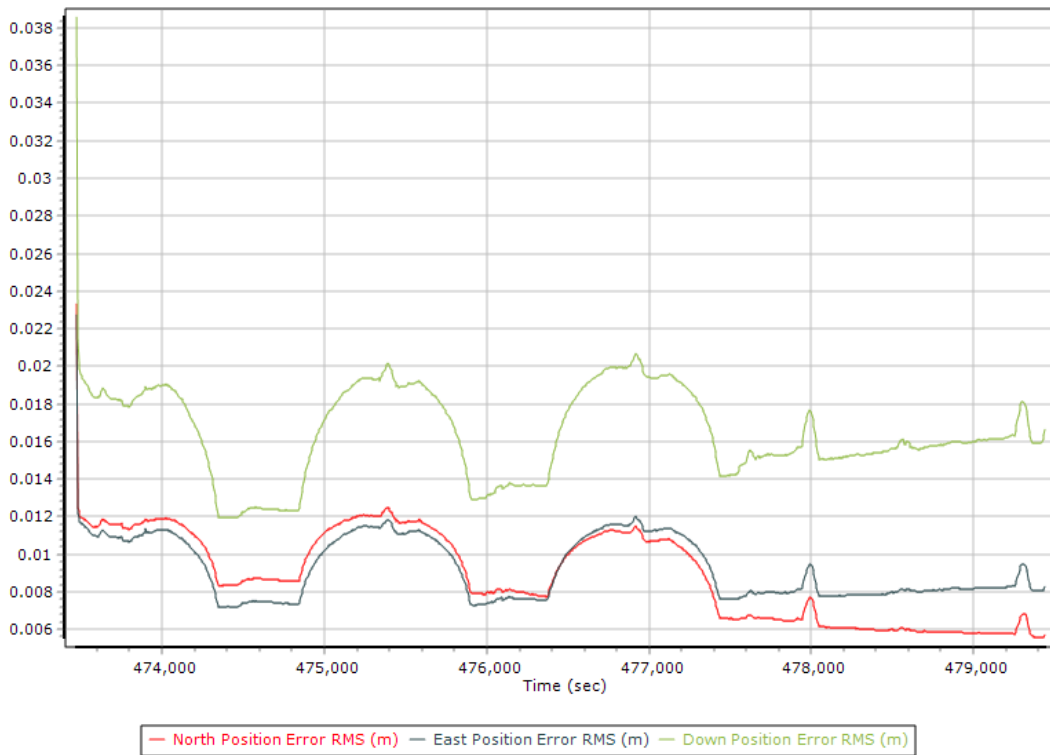
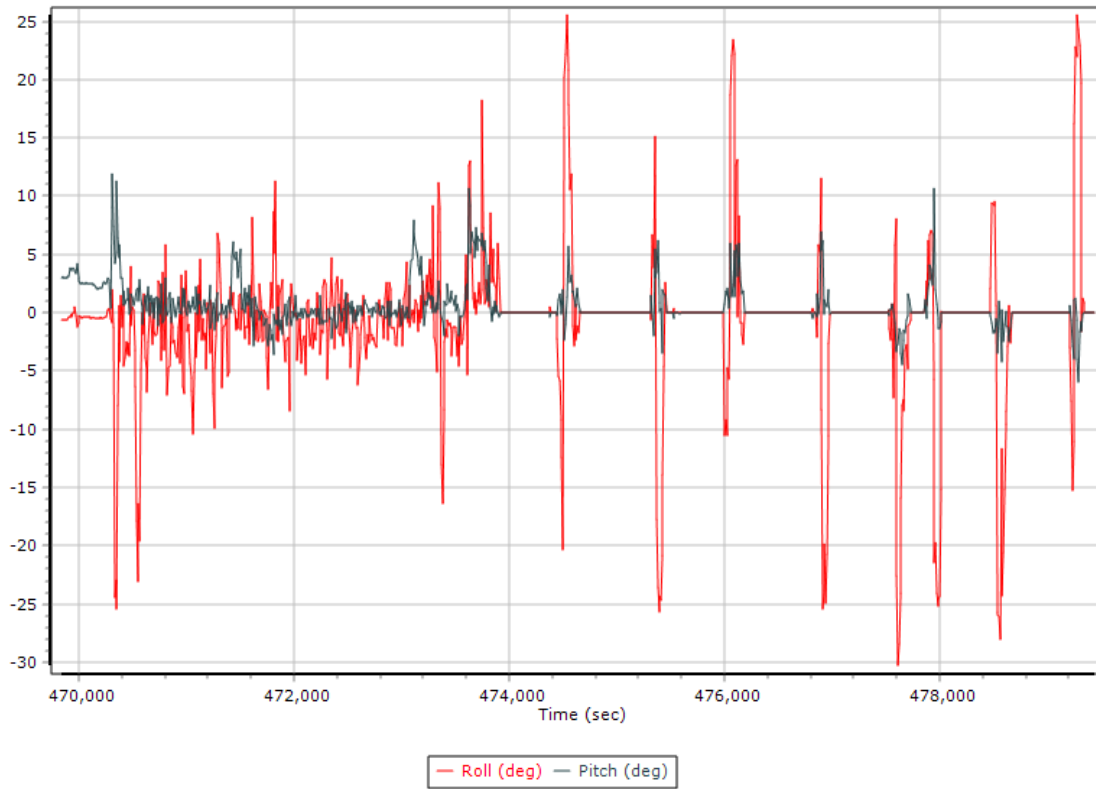
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

Timing

Start	473475.931	Data	Incr. (sec)
End	479445.000	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

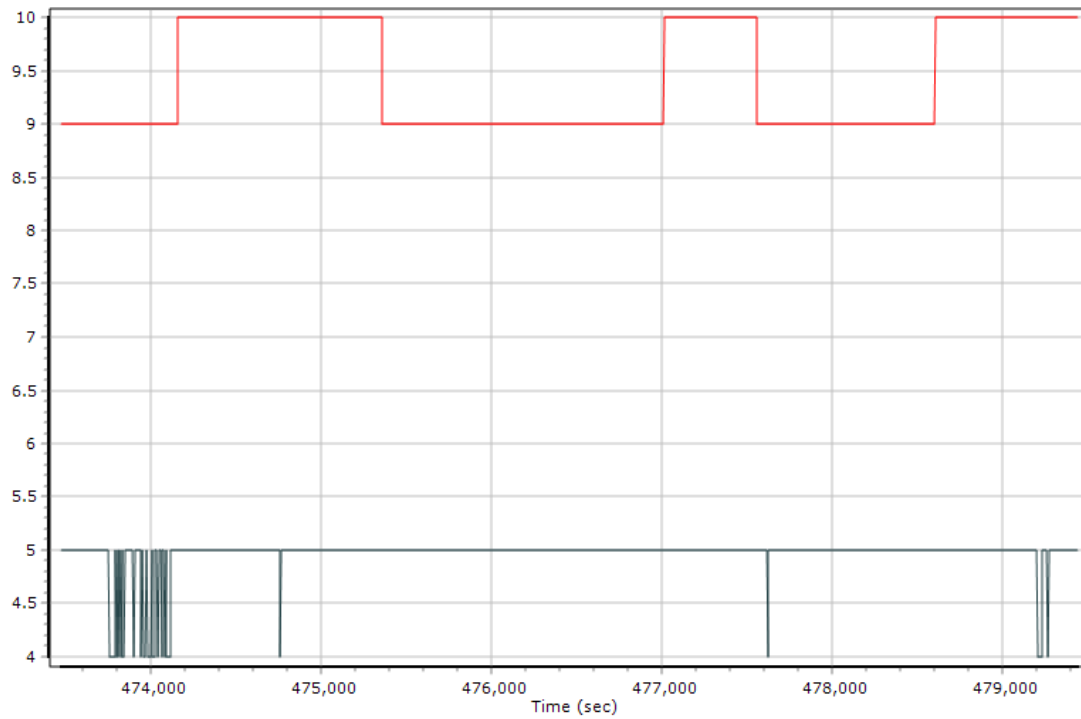
UTC Offset 18.000





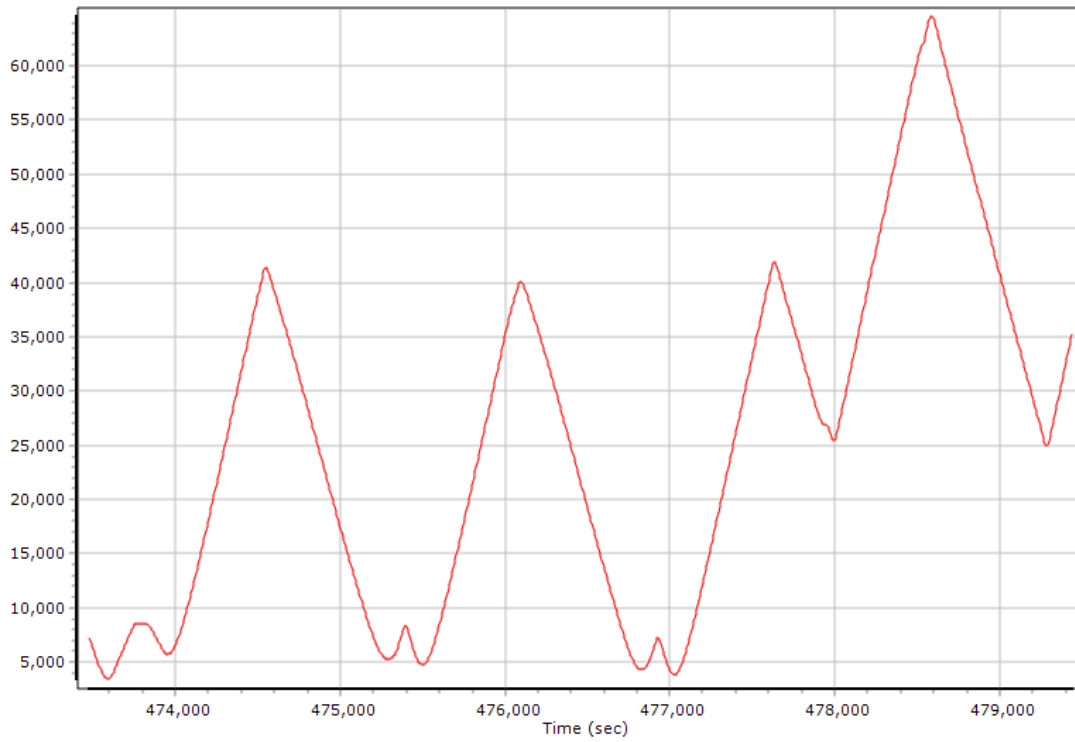


— North (m) — East (m) — Down (m) — DR mode

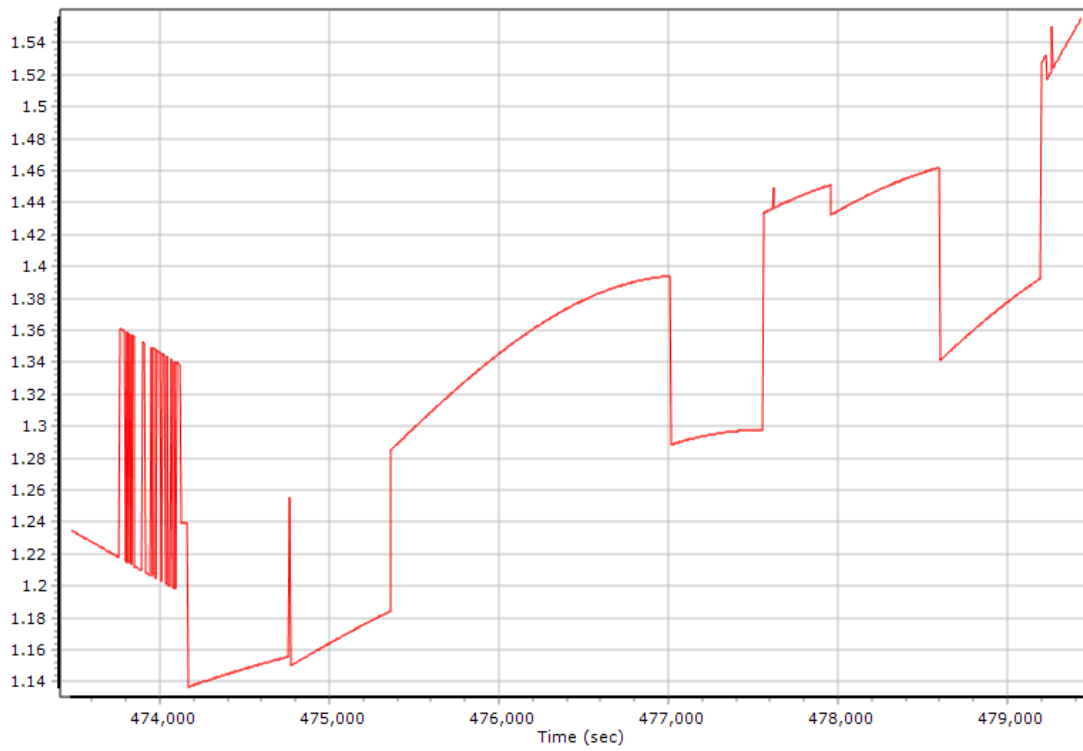


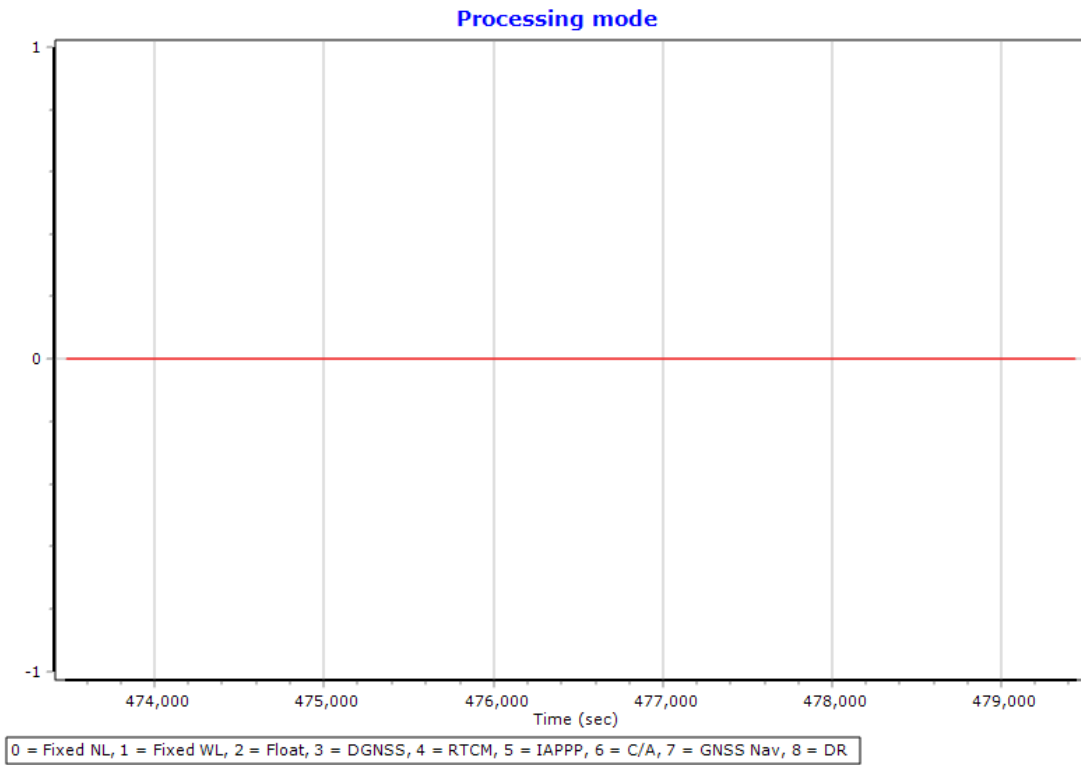
— Number of GPS Satellites — Number of GLONASS Satellites

Baseline Length (m)

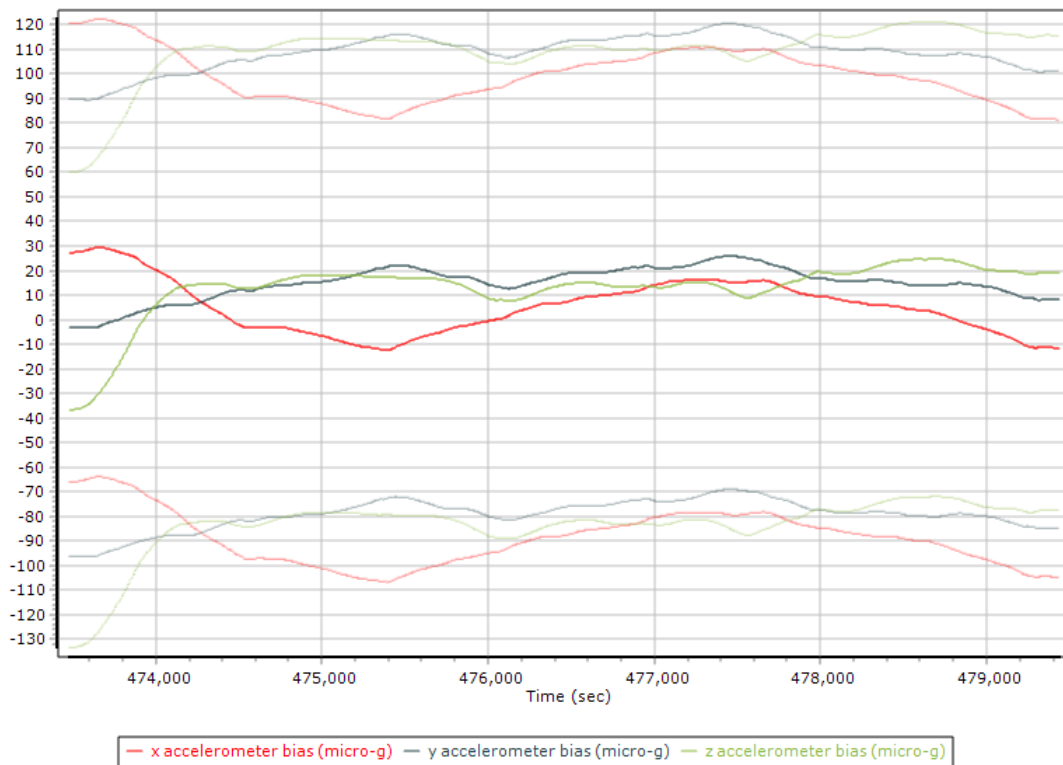


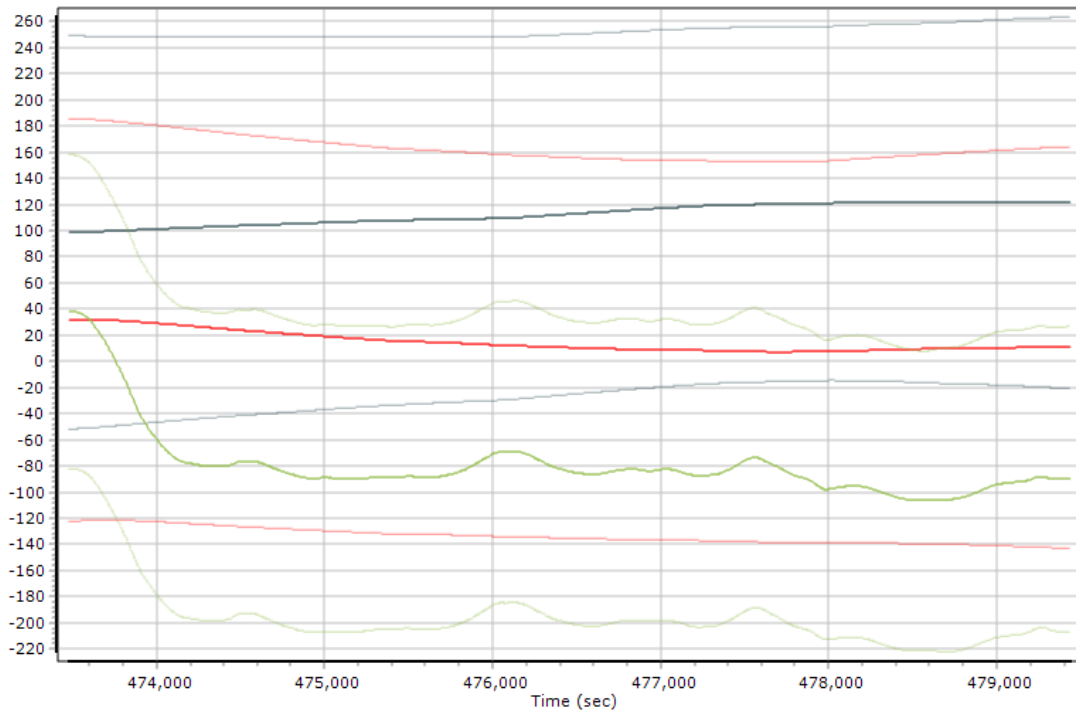
PDOP



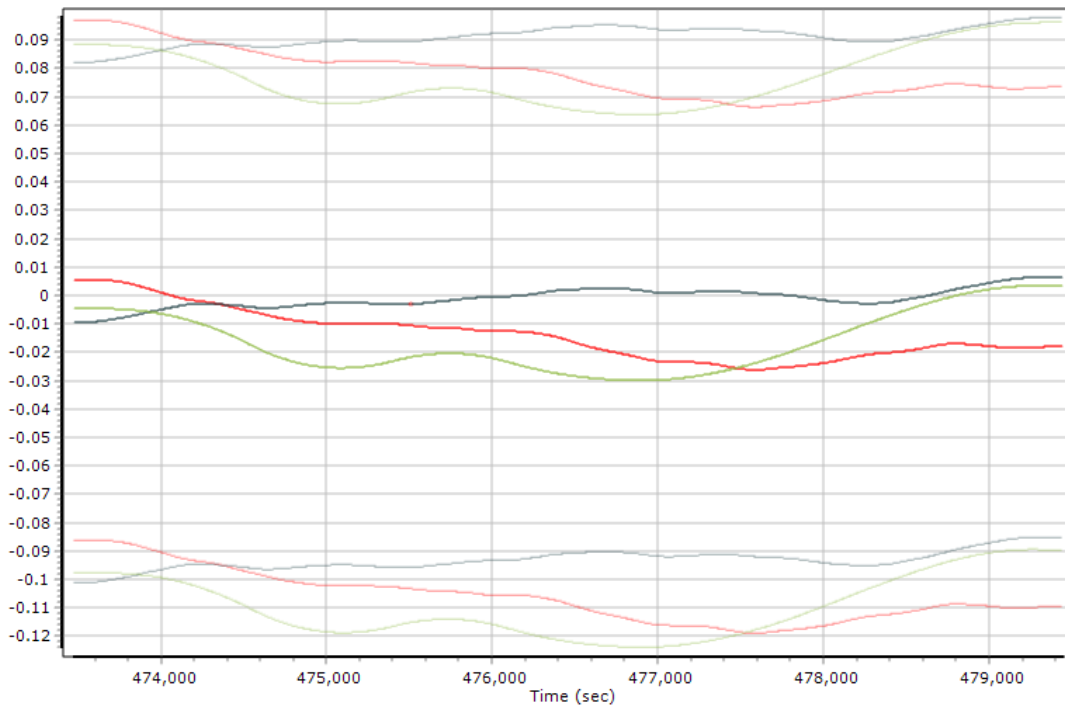


Sensor Errors

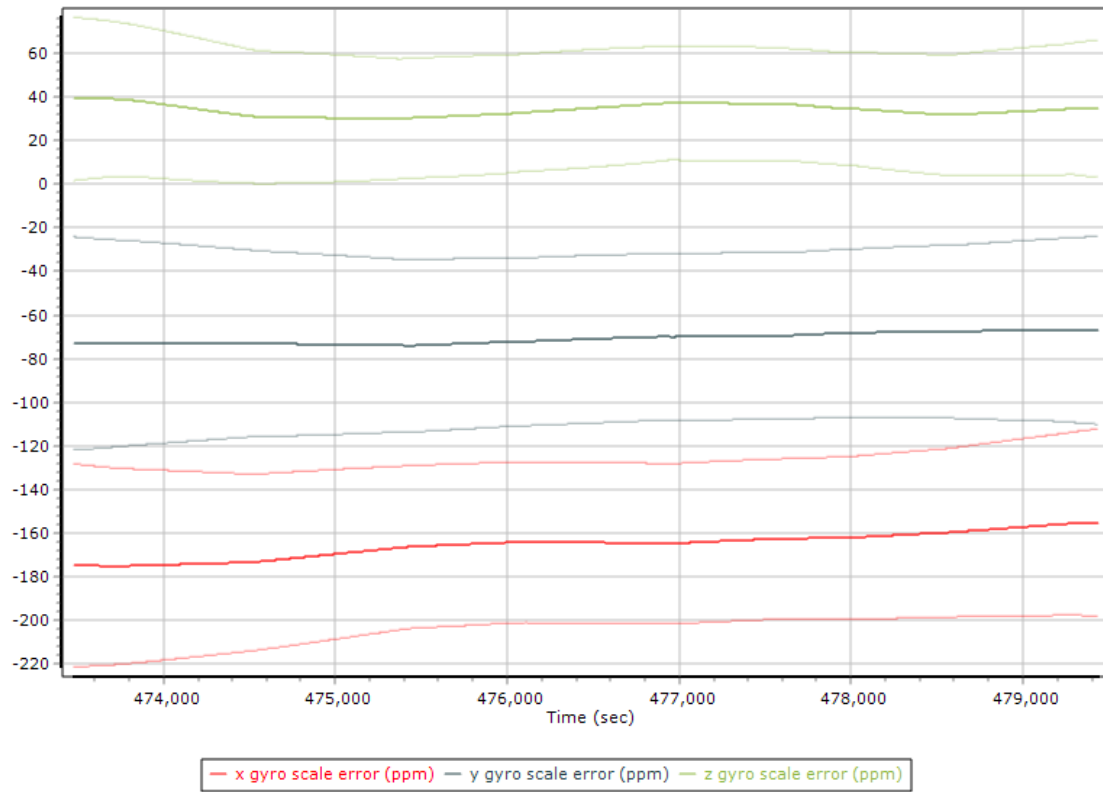




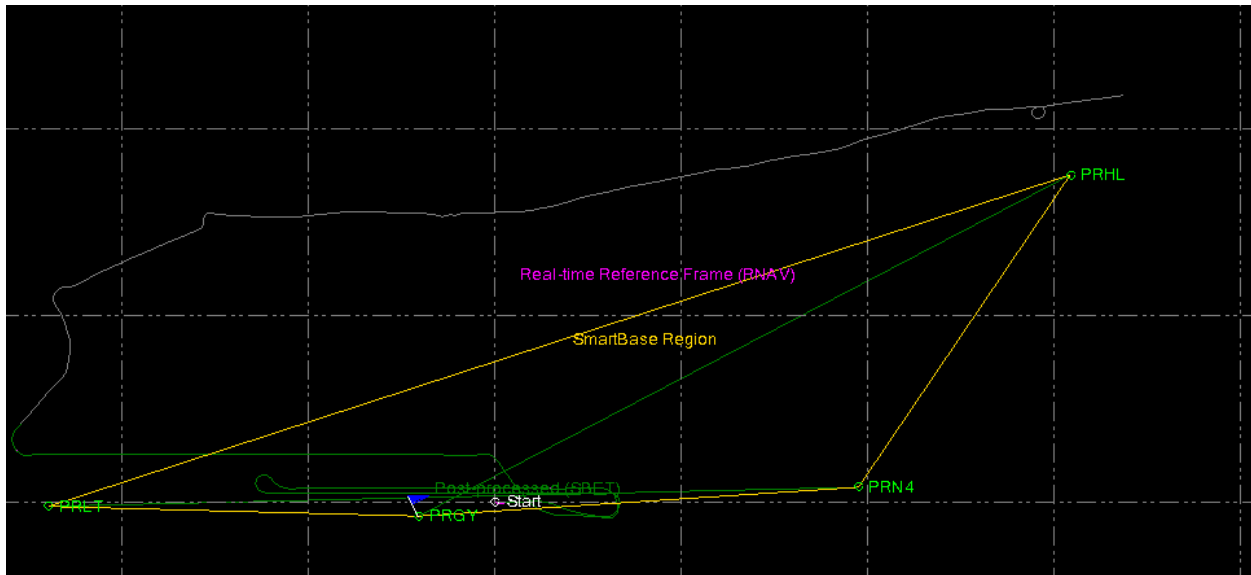
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

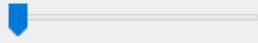


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



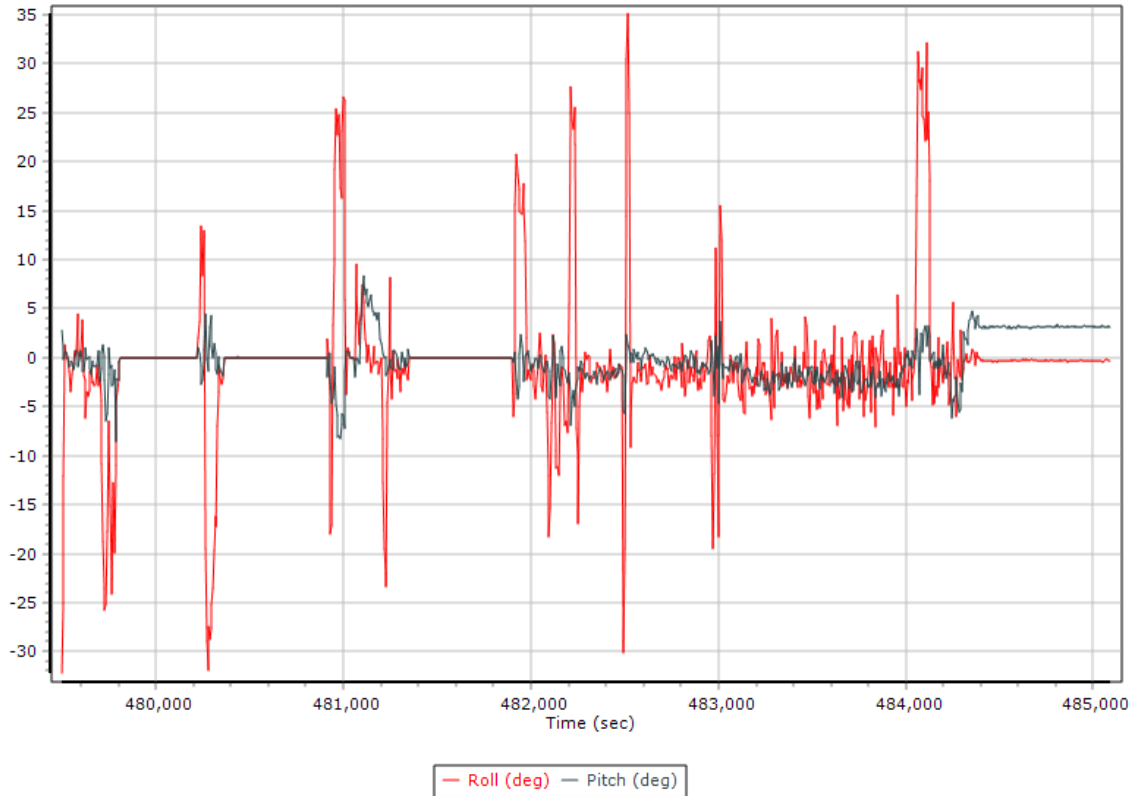
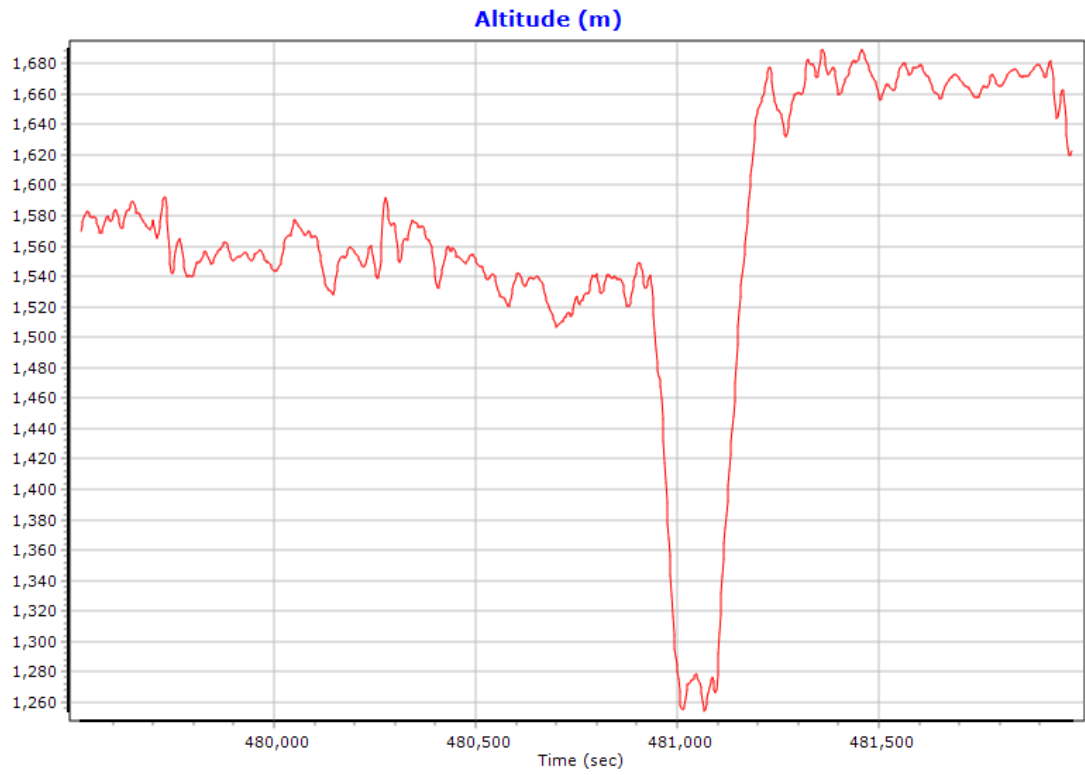
AZT18145A2

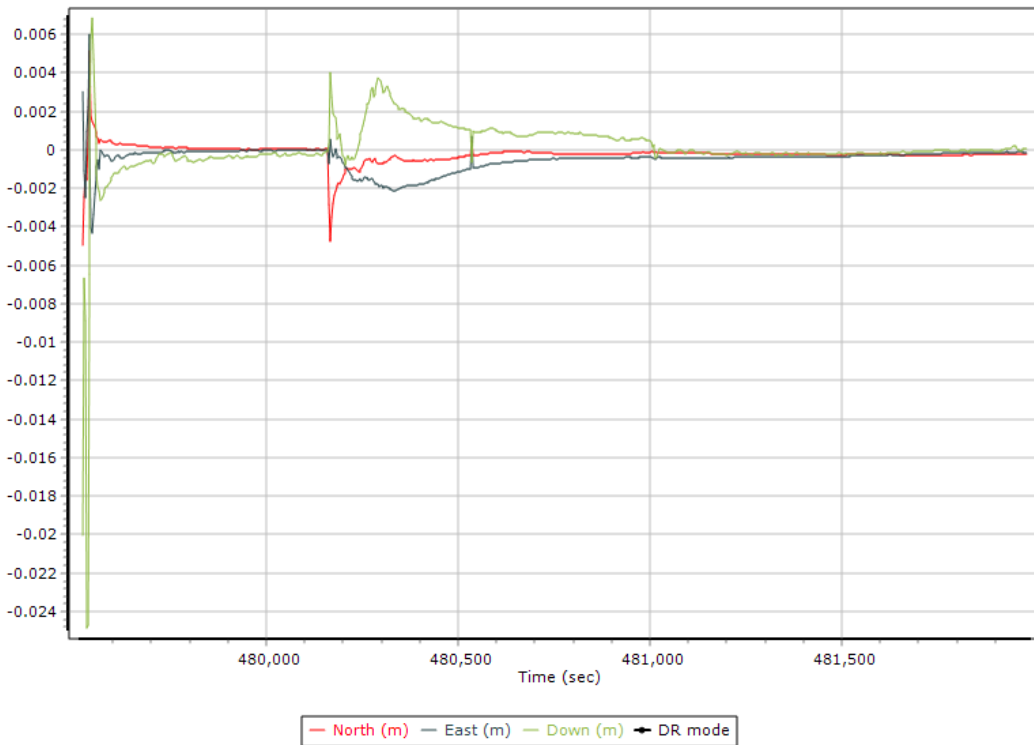
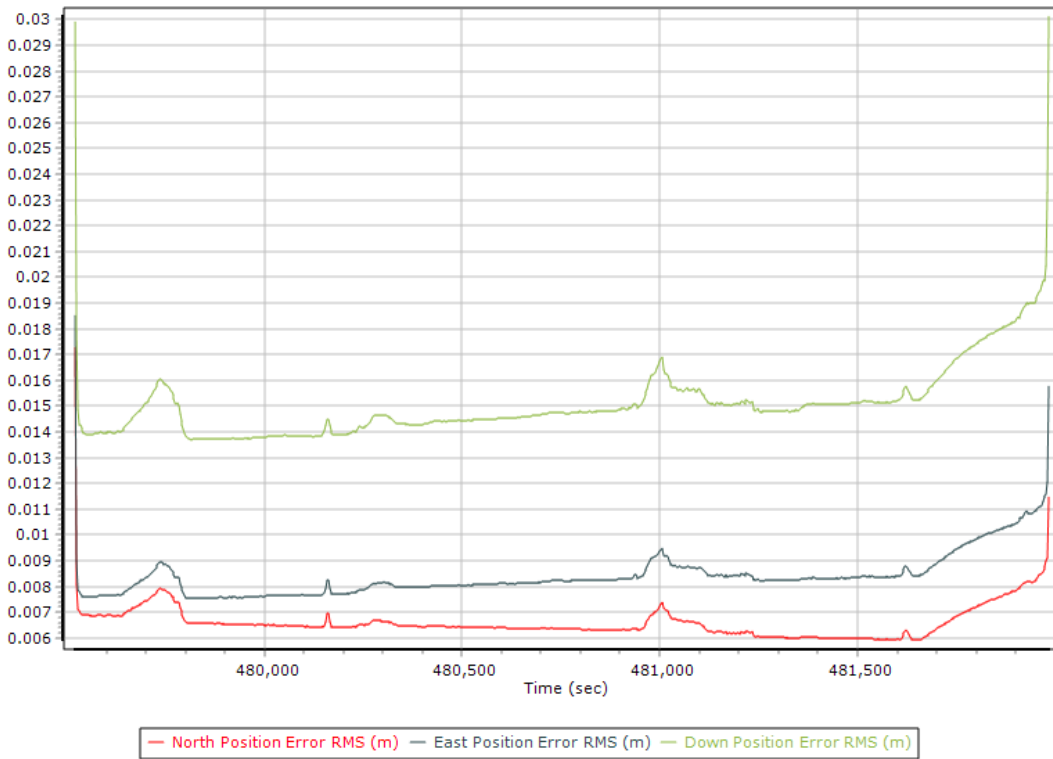


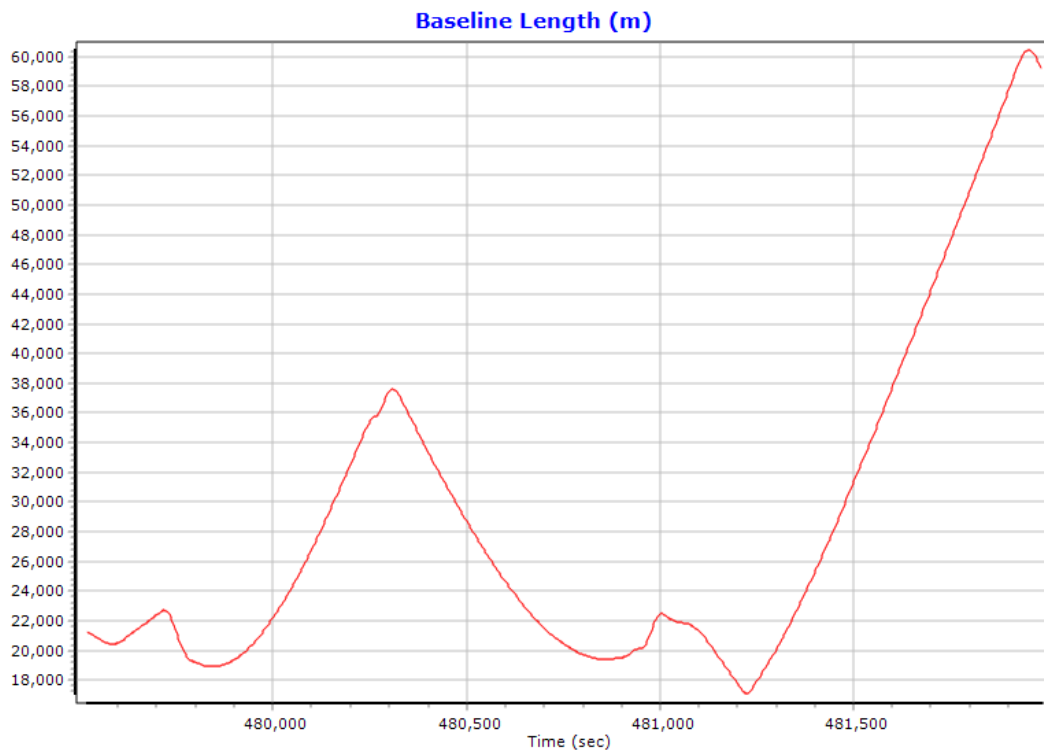
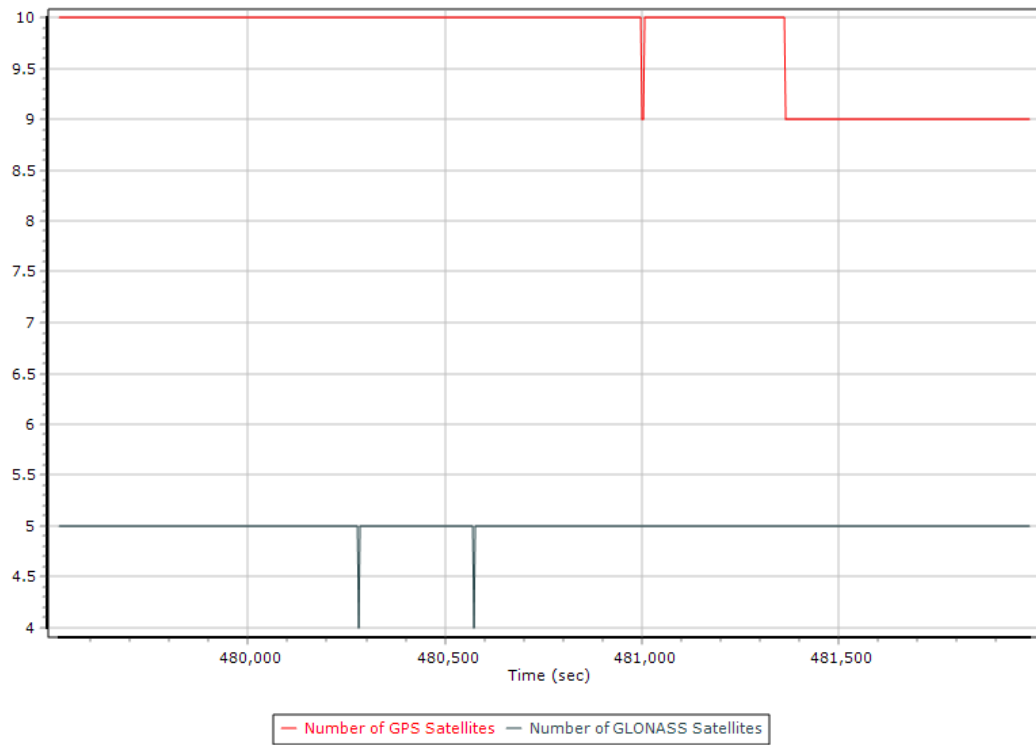
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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			
	<3cm 10cm 50cm 1m 10m		

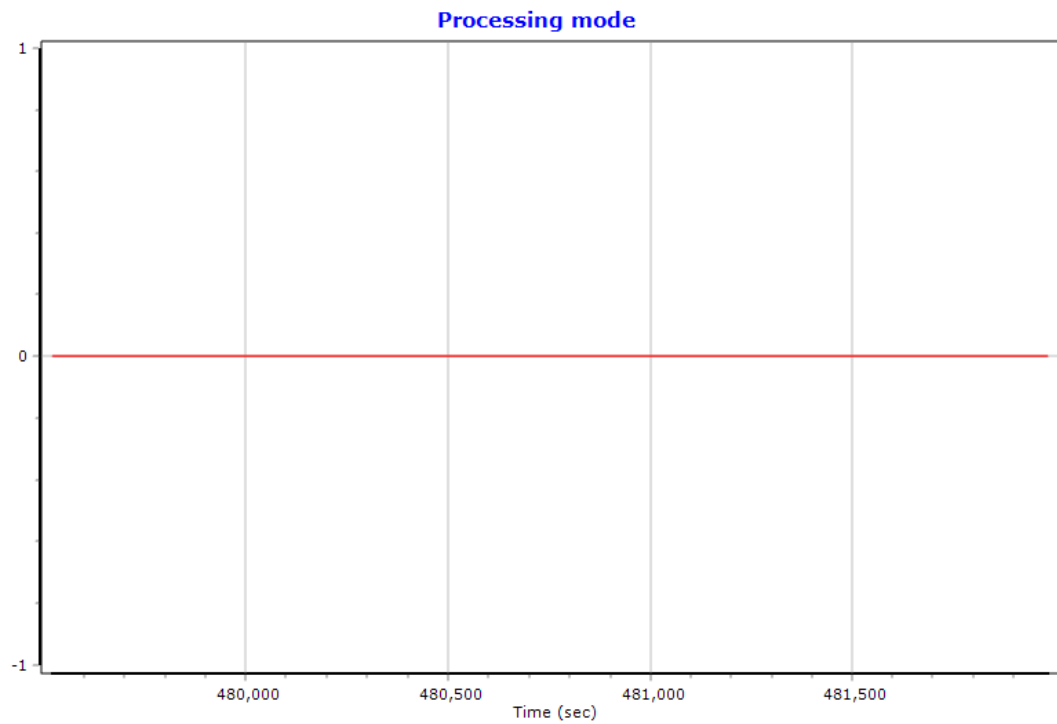
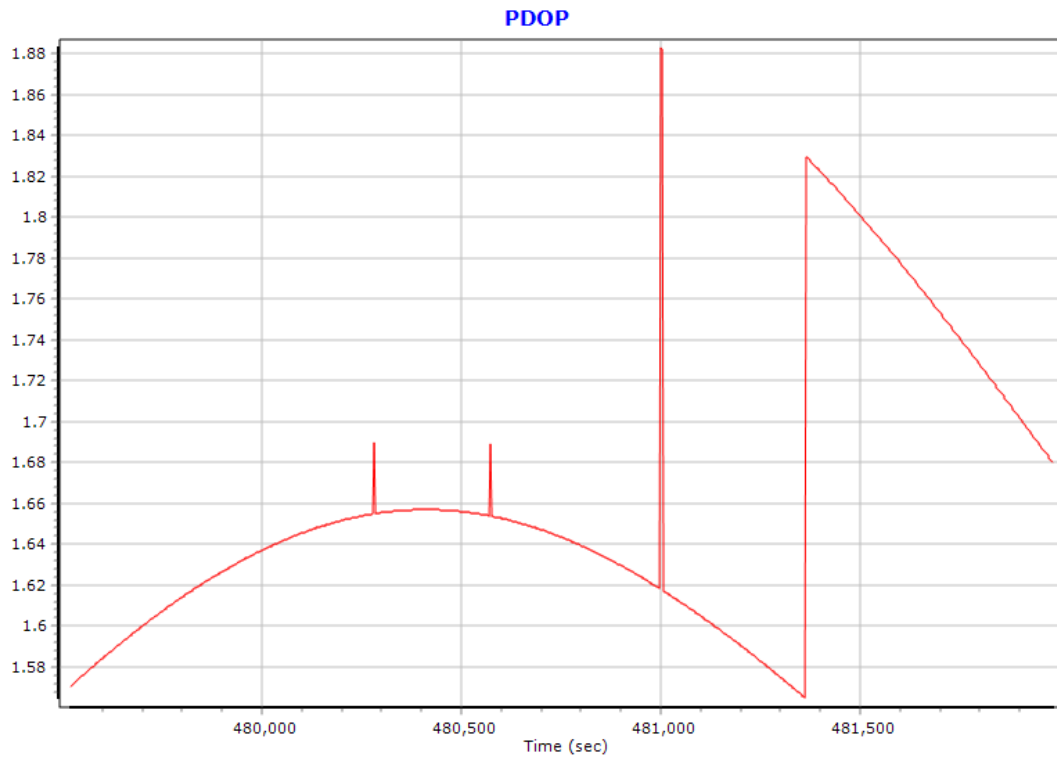
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

Timing									
Start	<input type="text" value="479501.000"/>								
End	<input type="text" value="481985.010"/>								
<input type="checkbox"/> Entire time interval									
<input checked="" type="checkbox"/> Seconds of start week									
UTC Offset	<input type="text" value="18.000"/>								
<table border="1"><thead><tr><th>Data</th><th>Incr. (sec)</th></tr></thead><tbody><tr><td>Output Record</td><td>0.005000</td></tr><tr><td>IMU</td><td>0.005000</td></tr><tr><td>Primary GNSS</td><td>1.000000</td></tr></tbody></table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000	
Data	Incr. (sec)								
Output Record	0.005000								
IMU	0.005000								
Primary GNSS	1.000000								



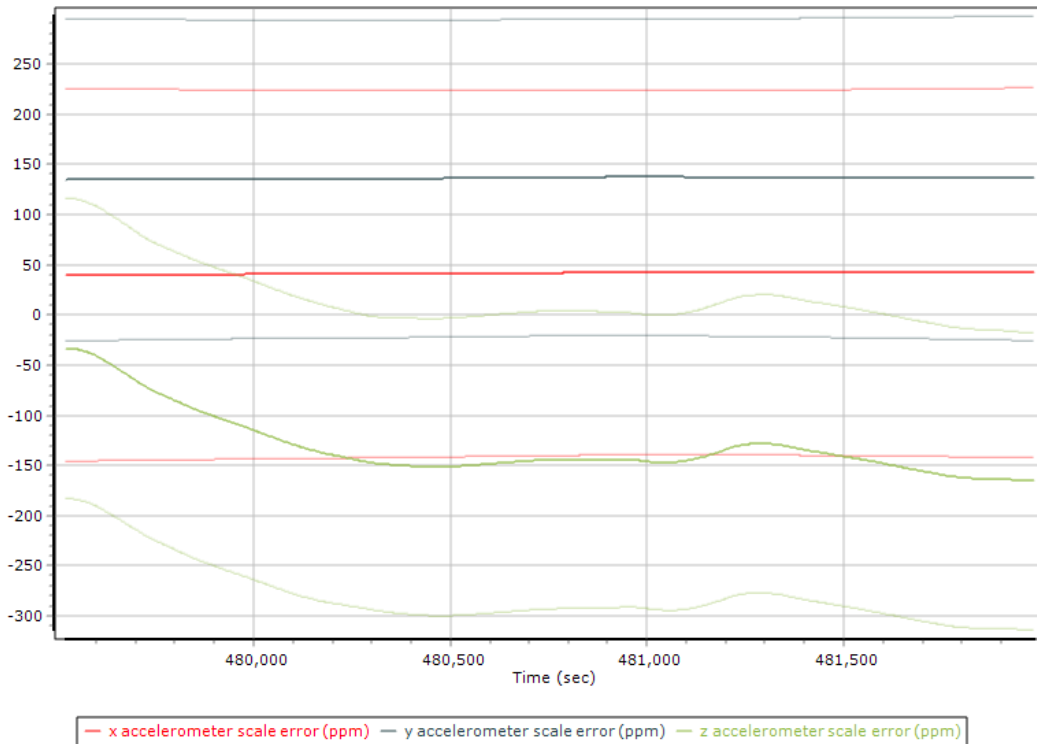
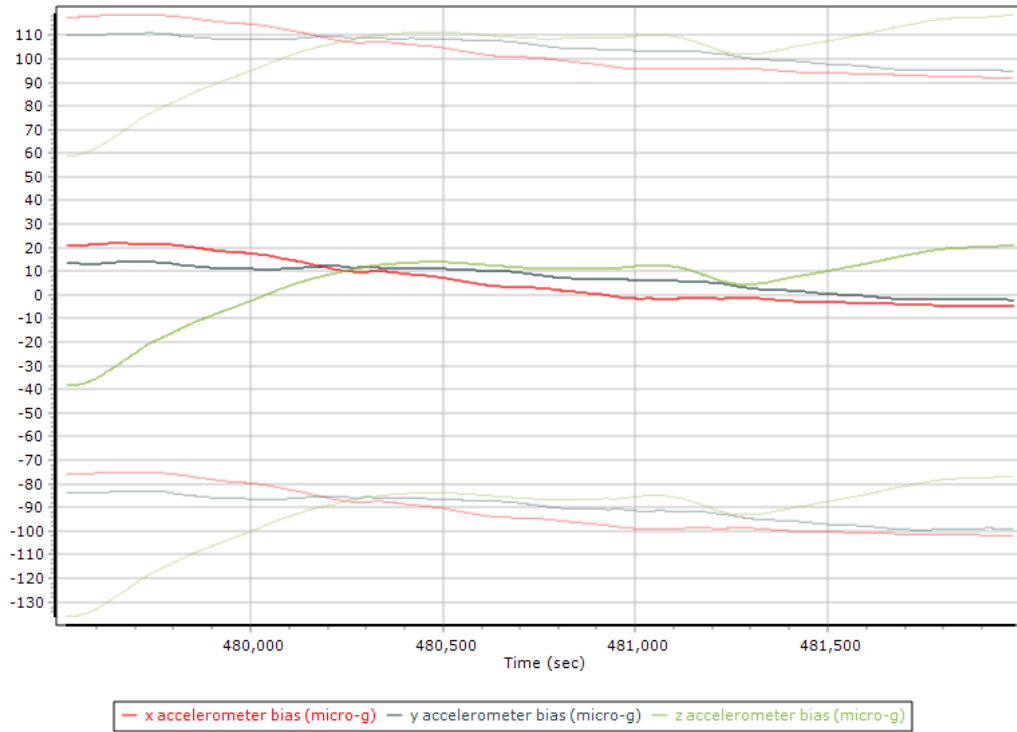


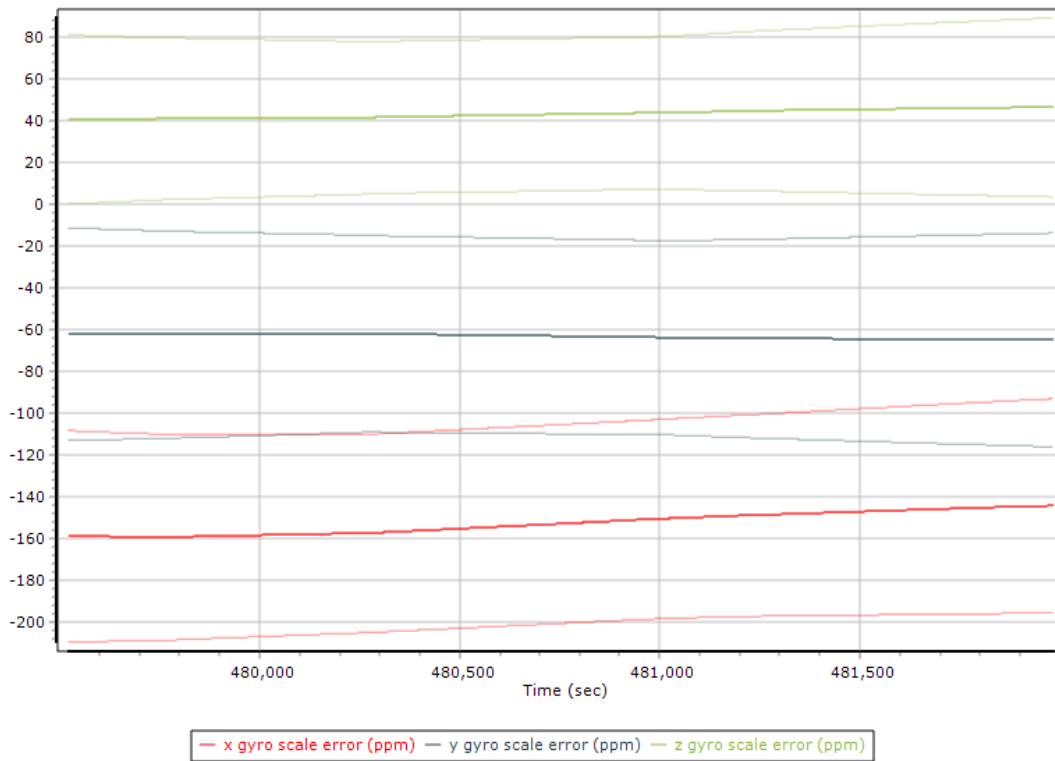
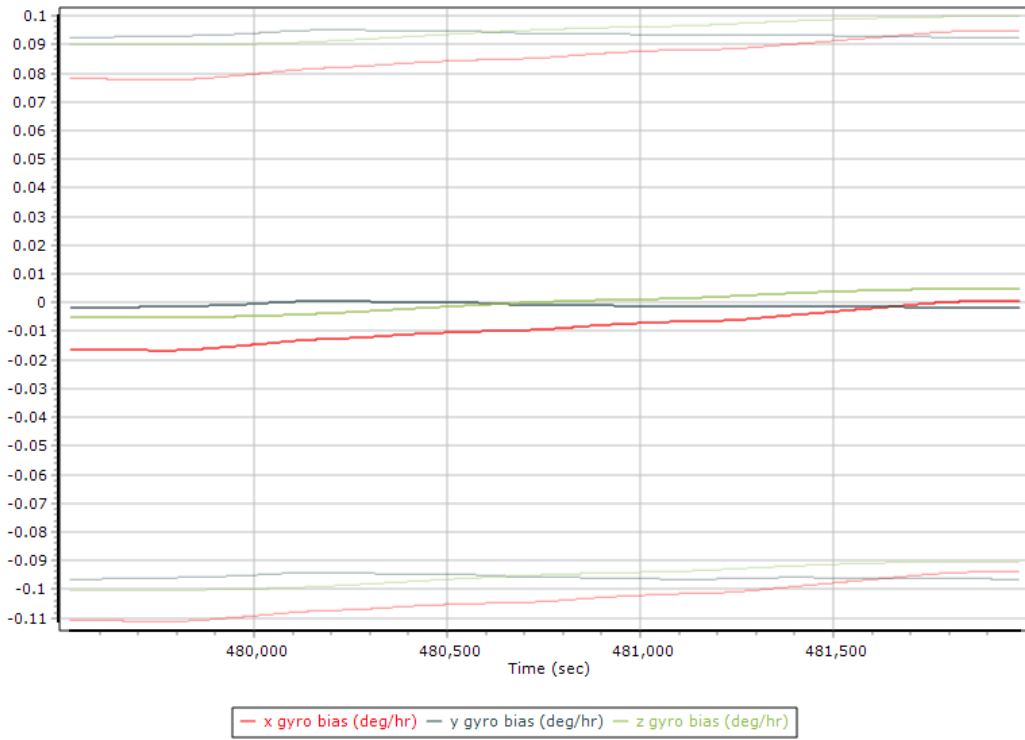




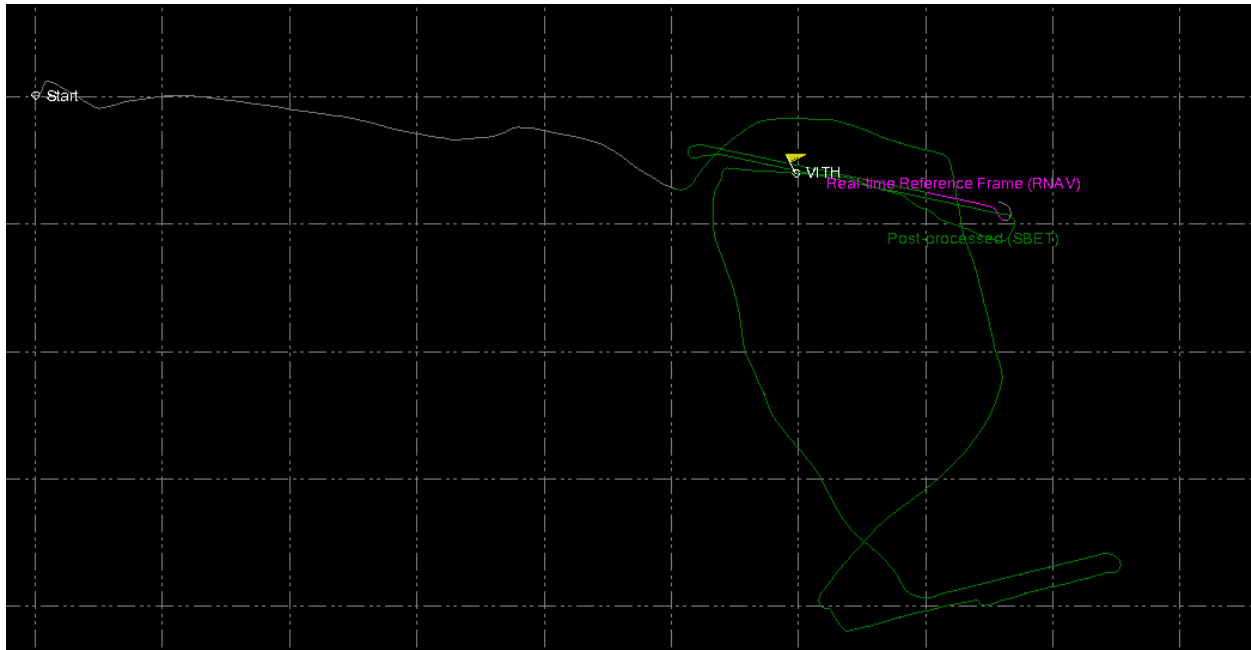
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





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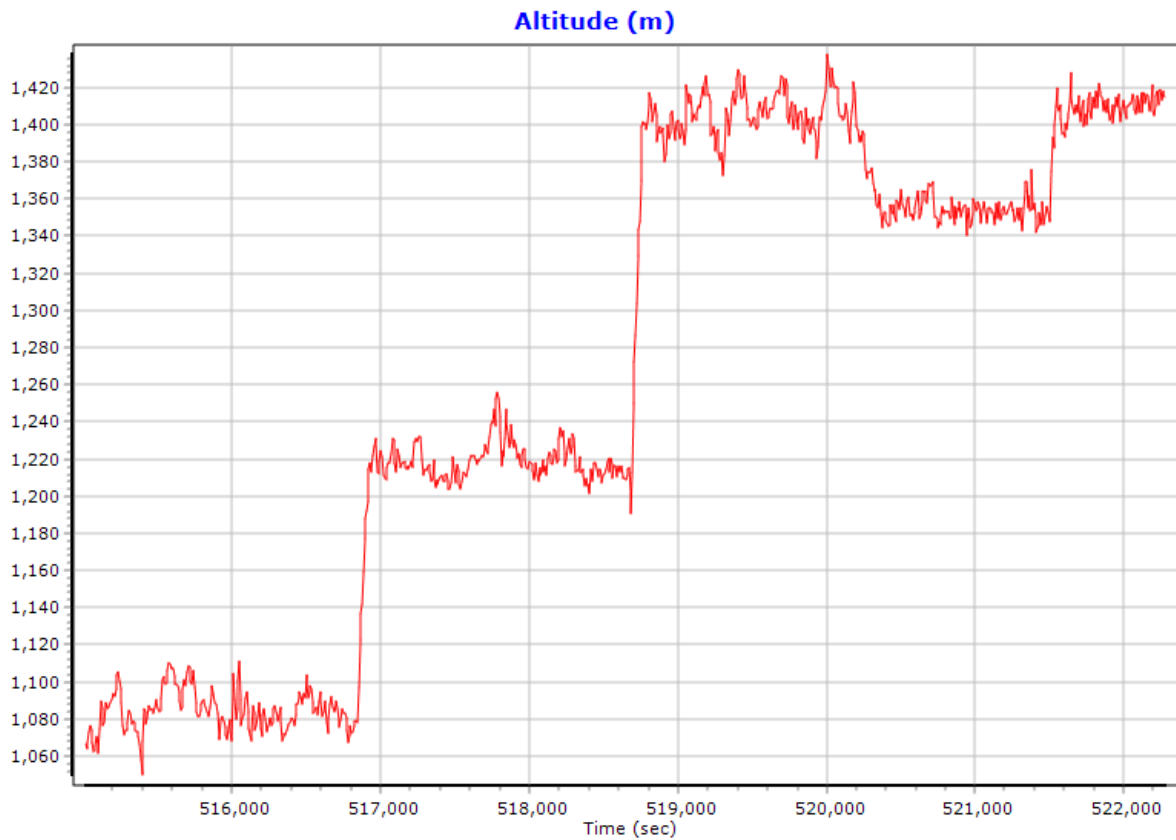
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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="-0.738 m"/>	Z	<input type="text" value="0.000 deg"/>
Standard Deviation	<input max="10" min="0.03" type="range" value="0.03"/>		
	<p><3cm 10cm 50cm 1m 10m</p>		

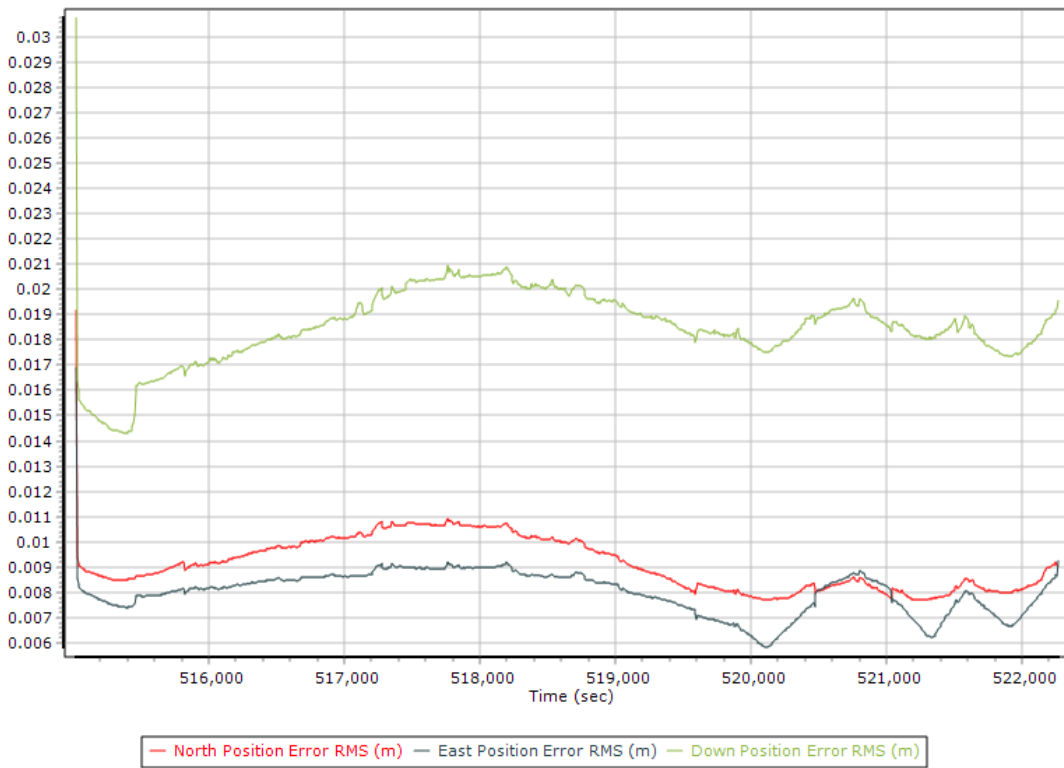
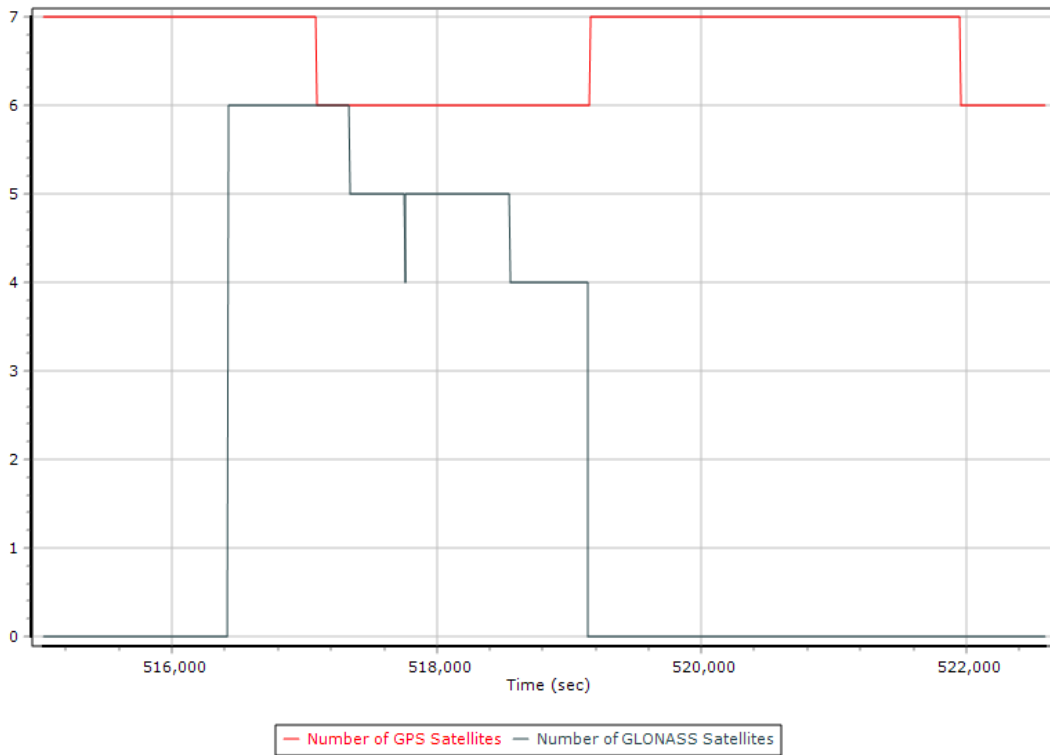
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

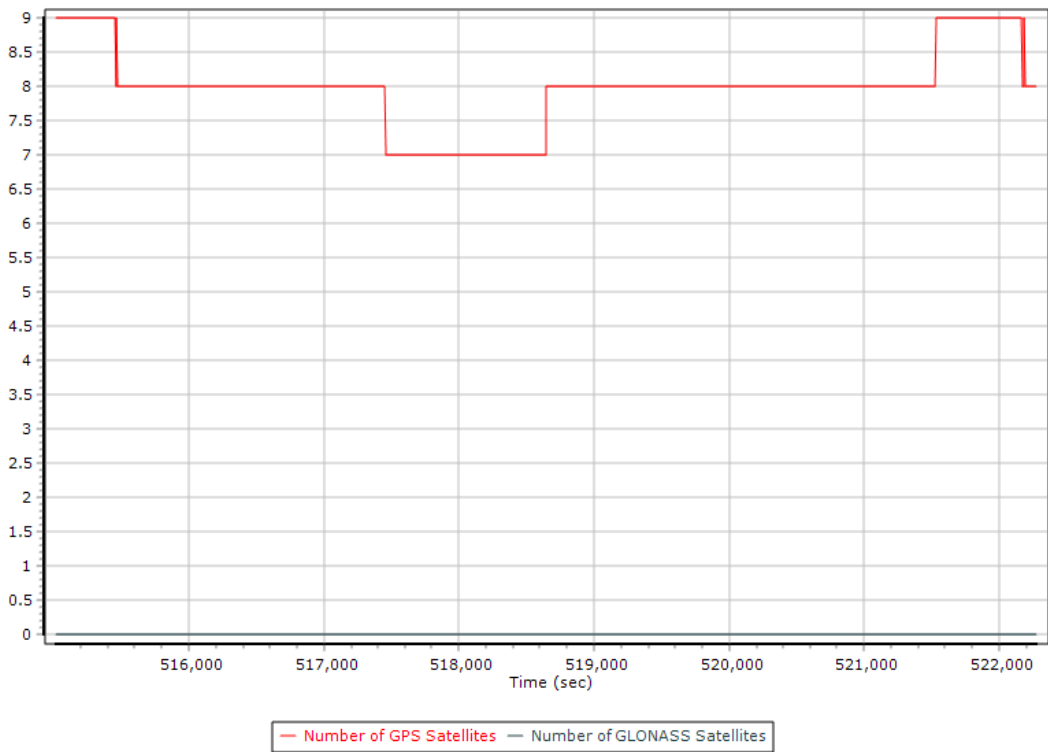
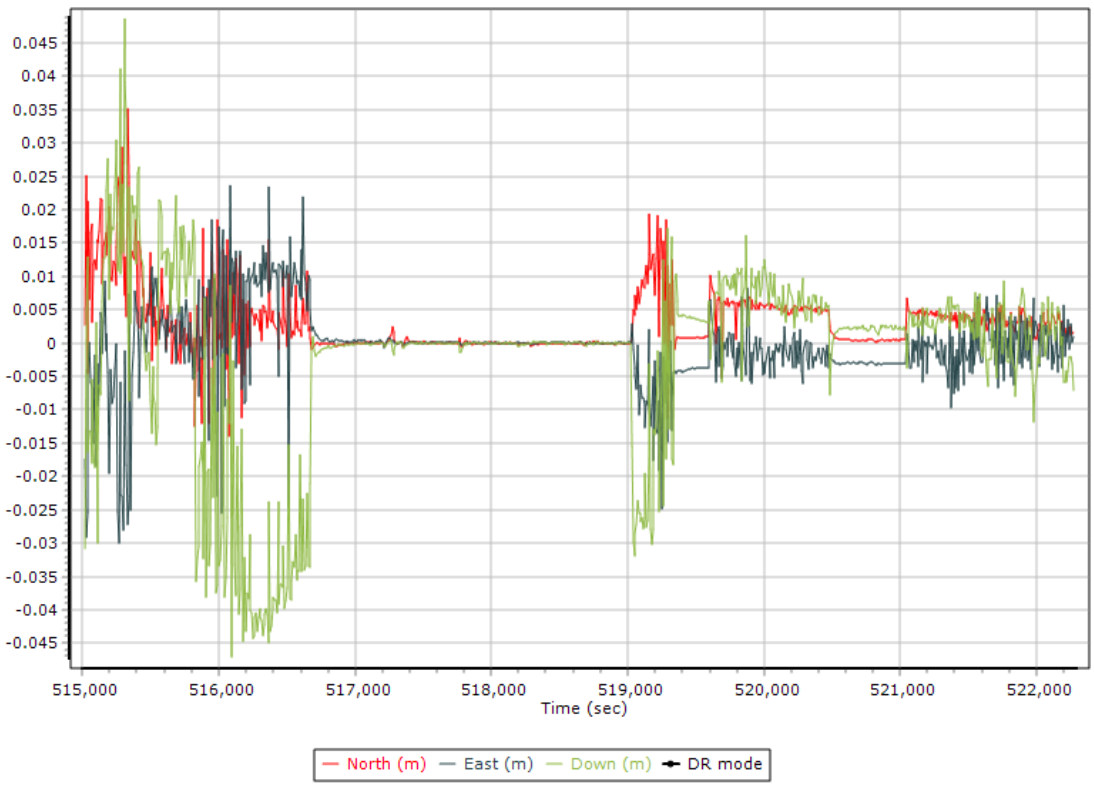
Timing

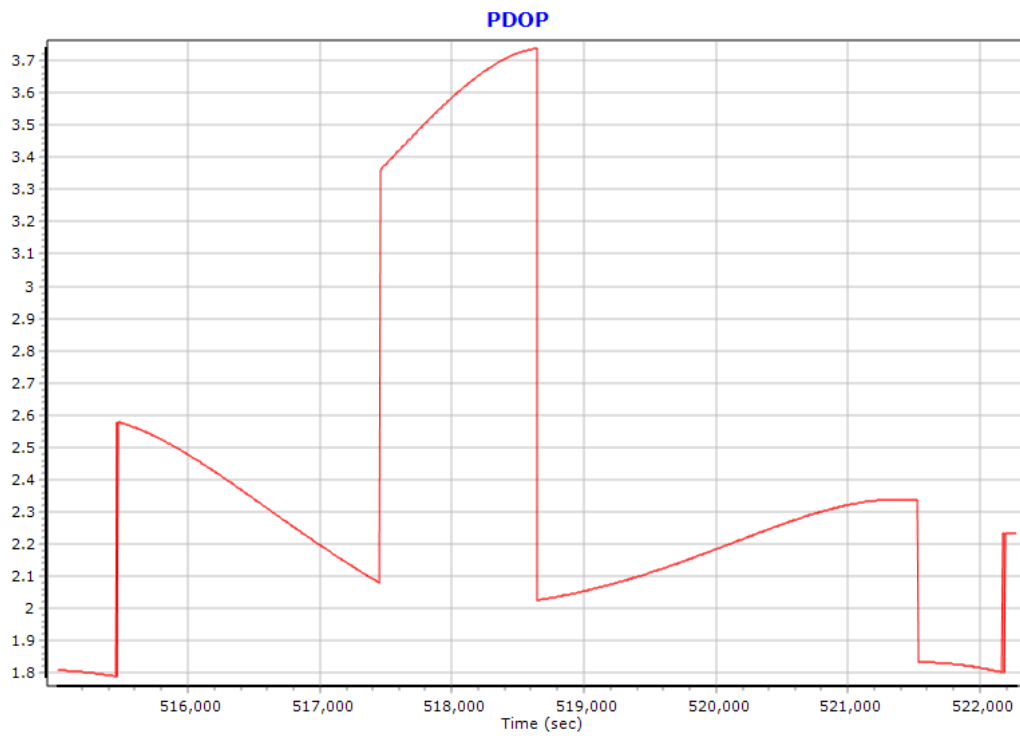
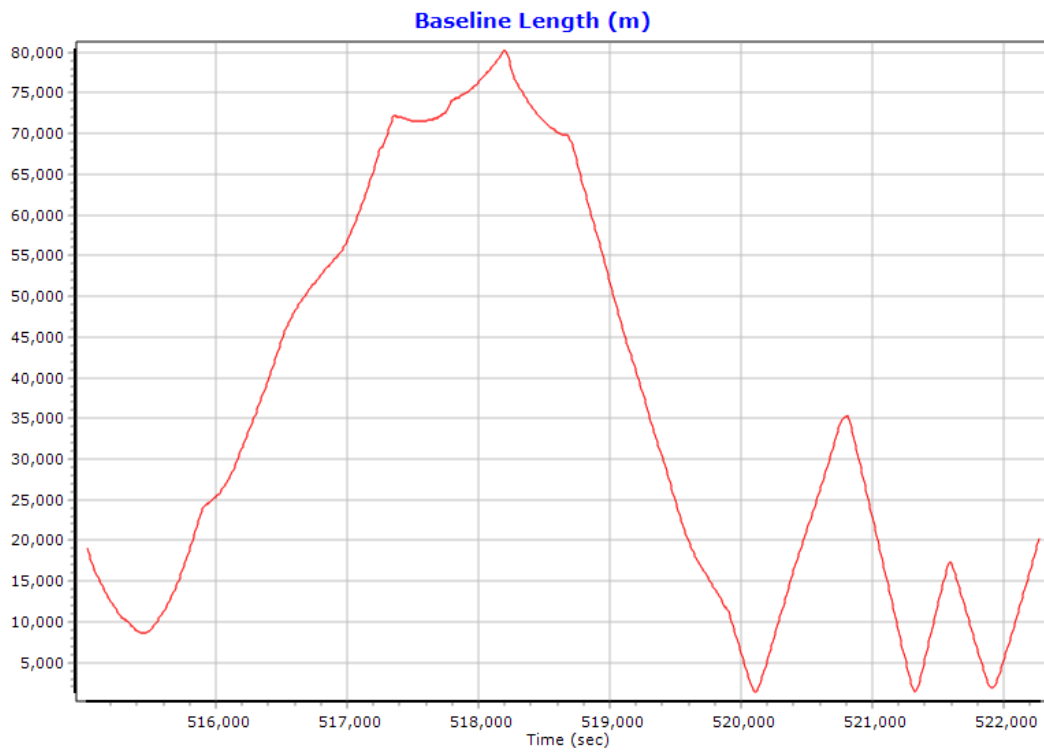
Start	515014.000	Data	Incr. (sec)
End	522286.000	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

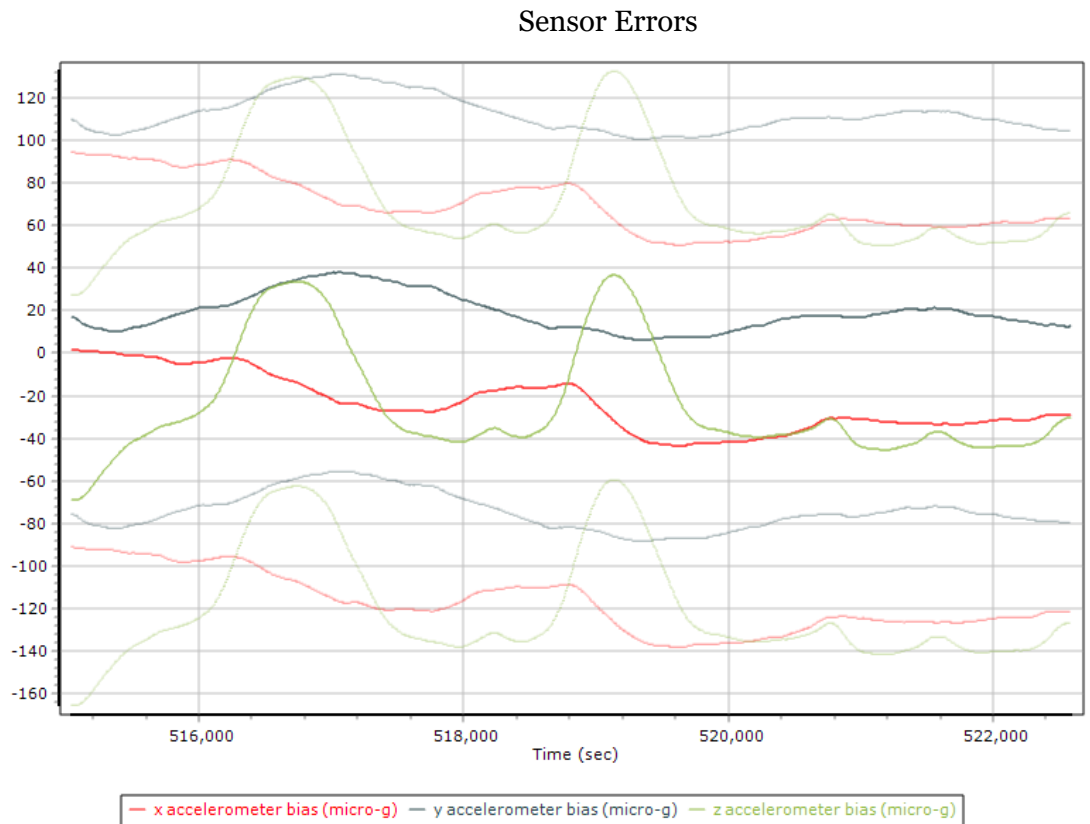
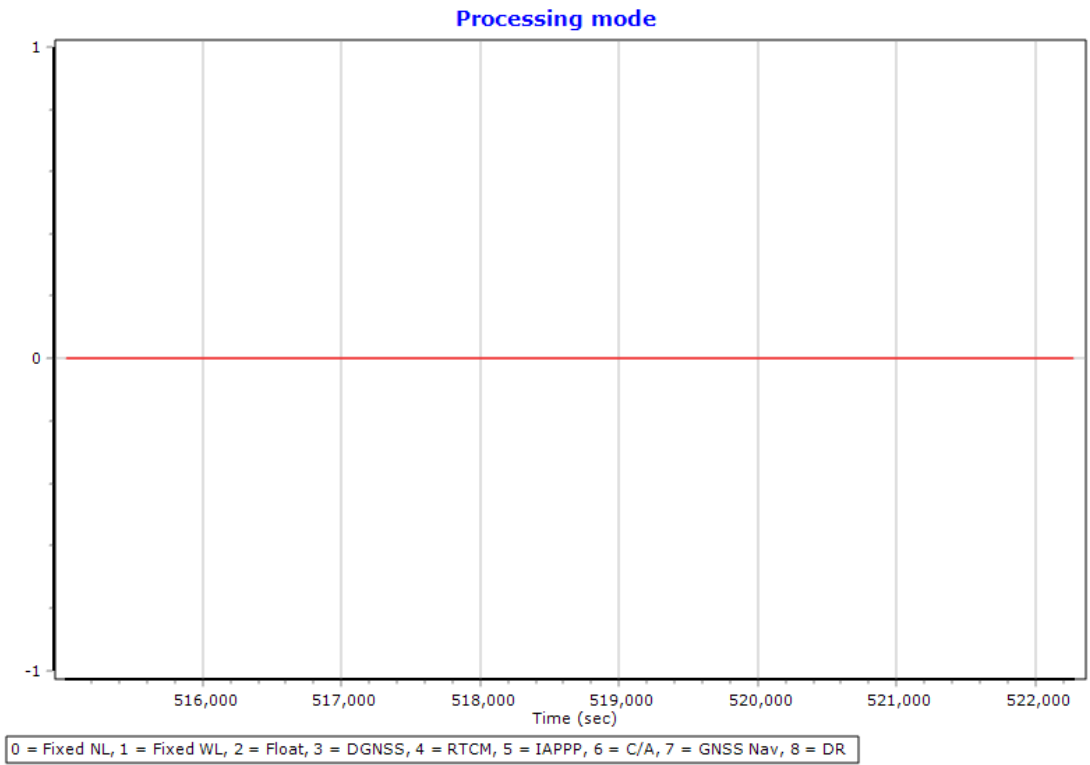
UTC Offset 18.000

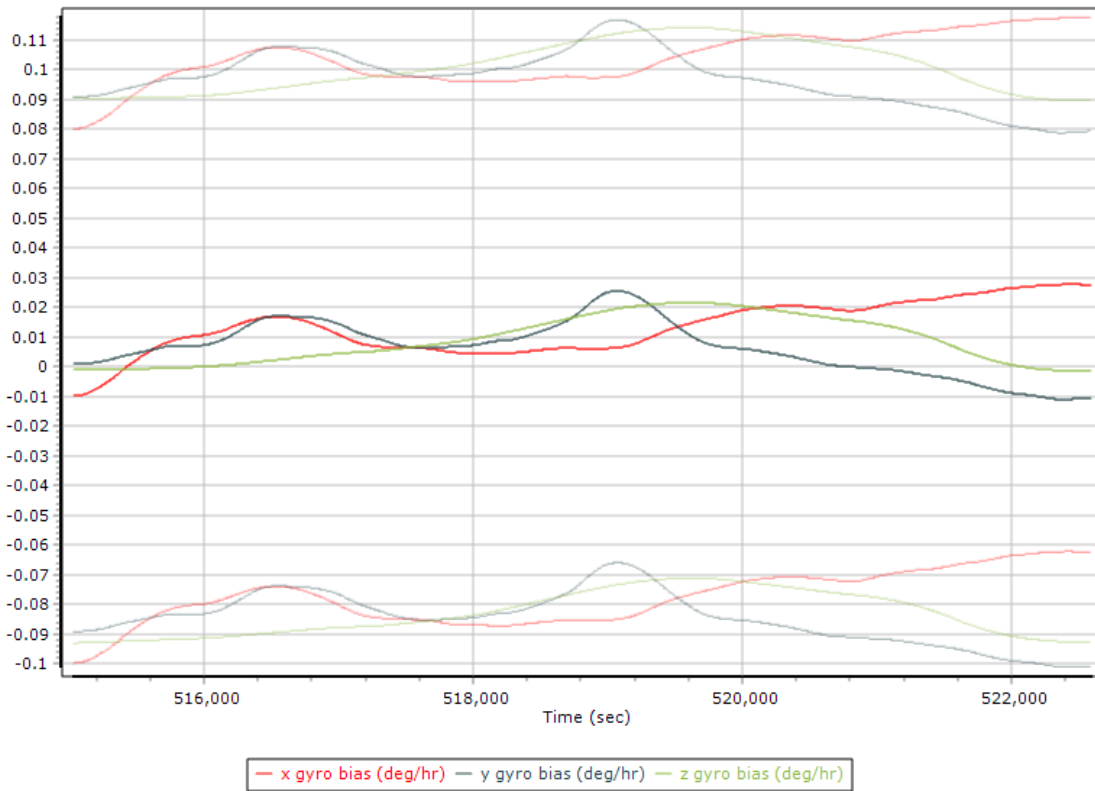
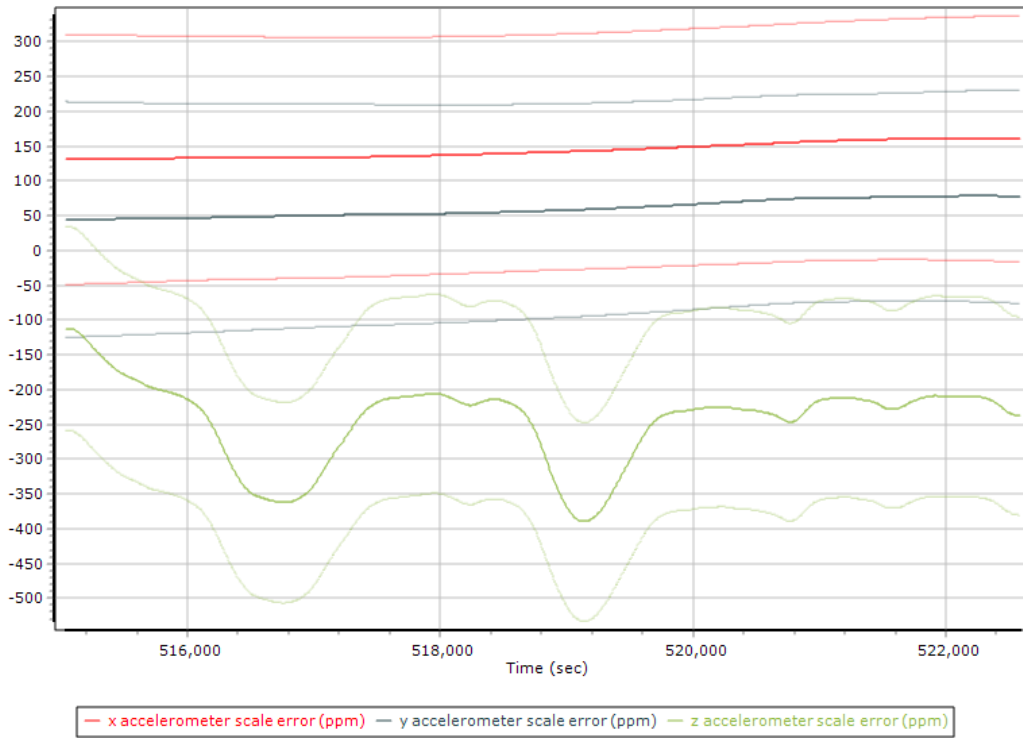


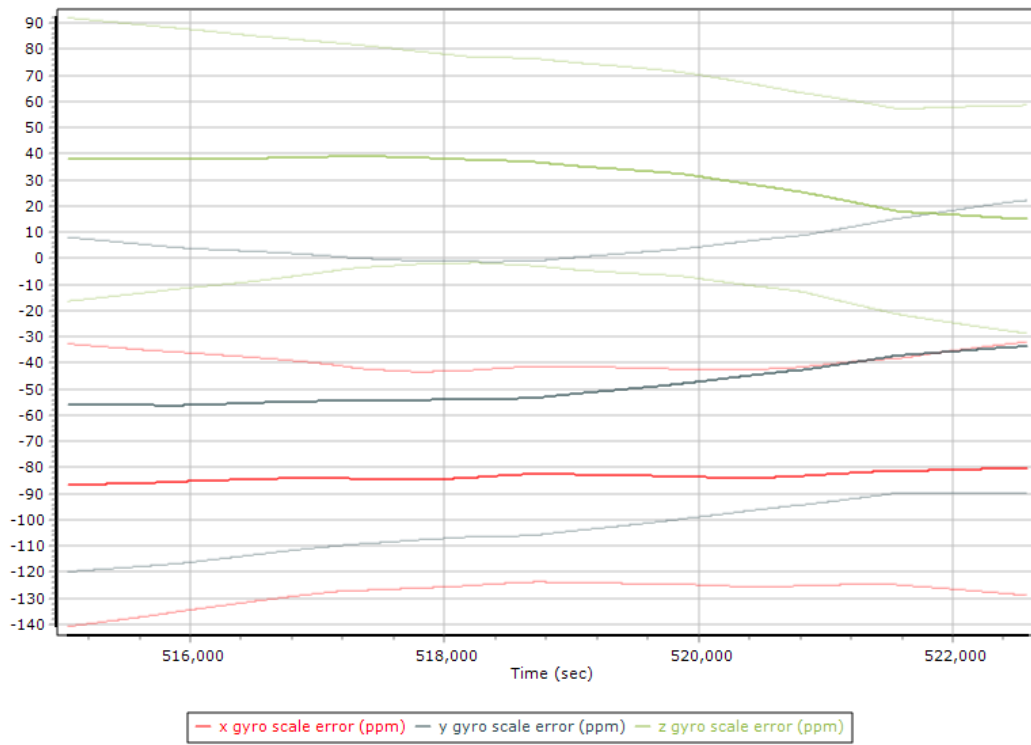




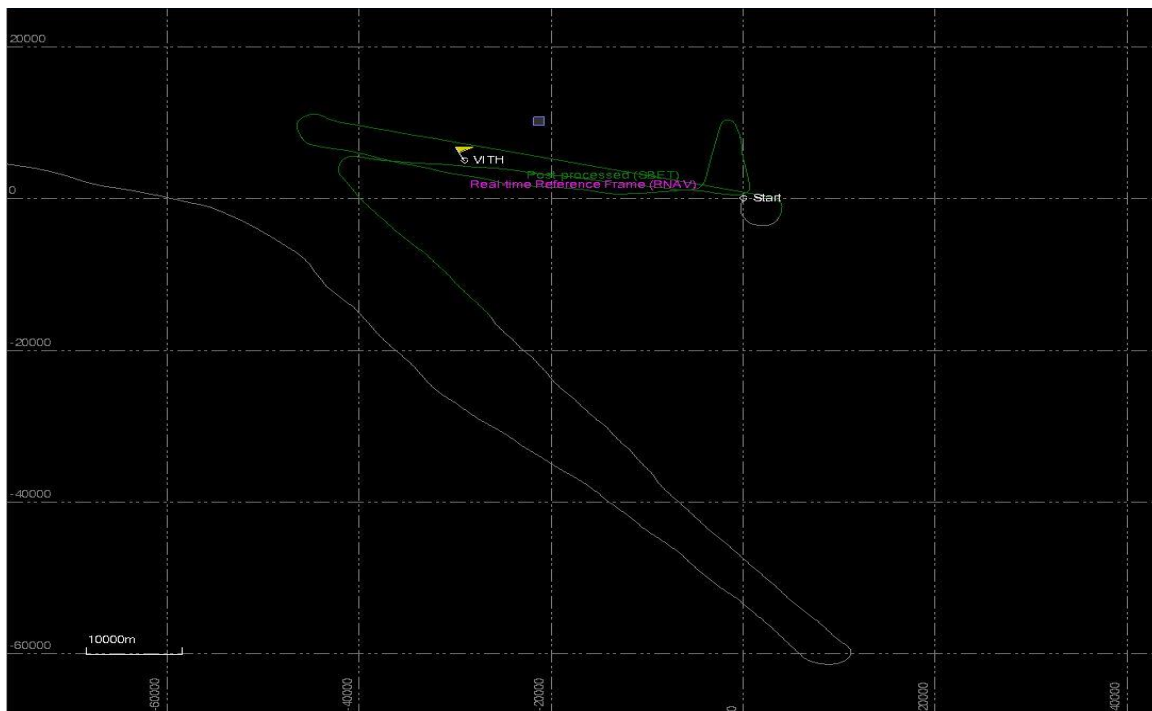


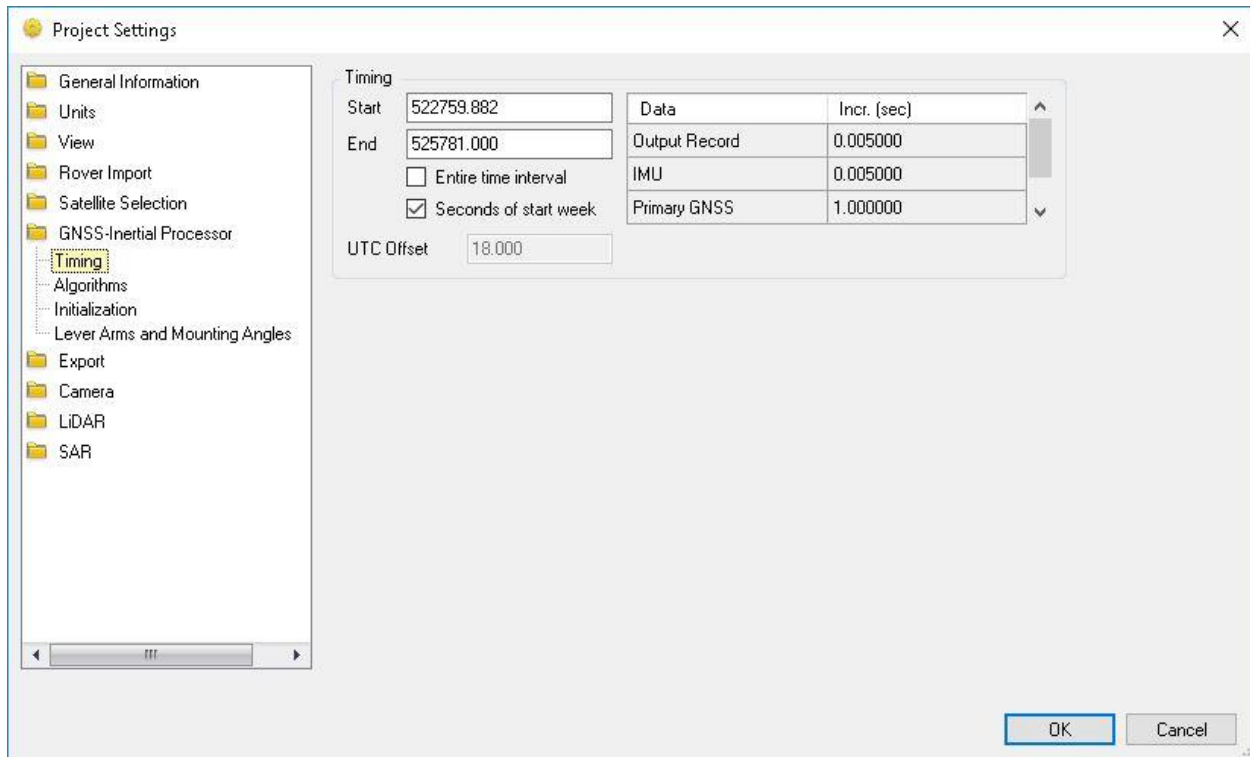
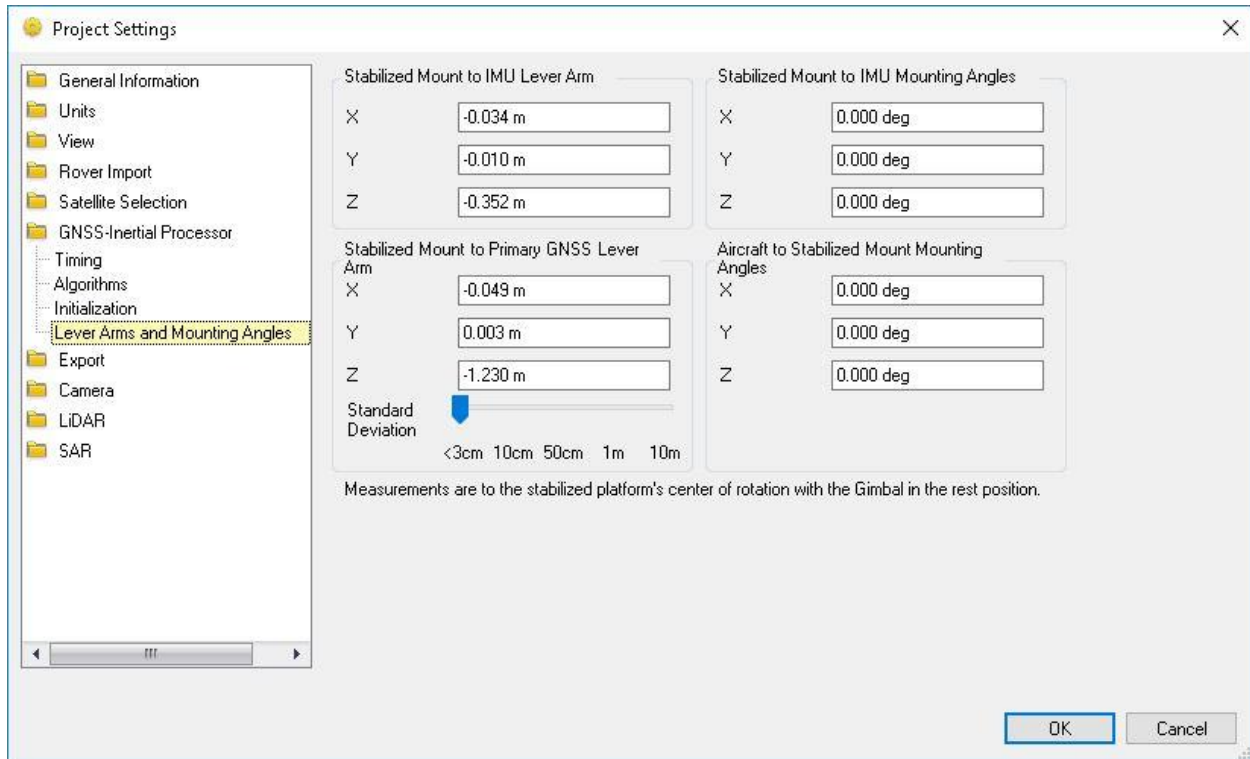


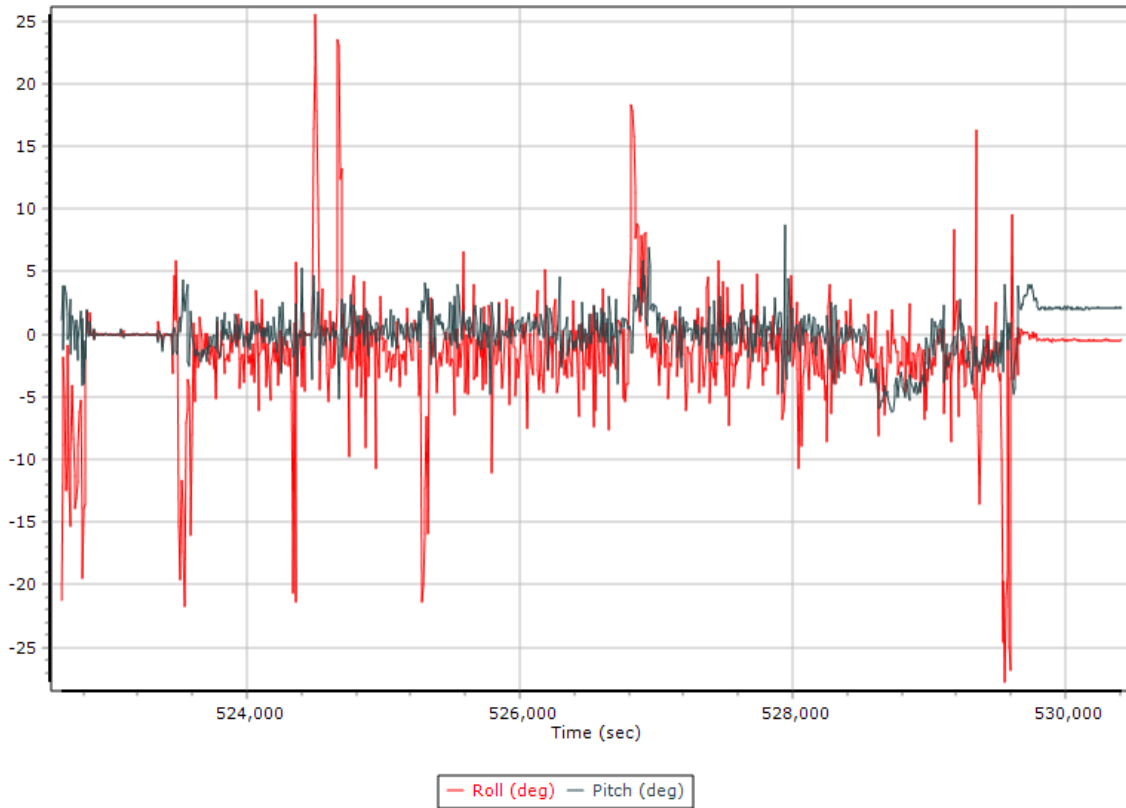
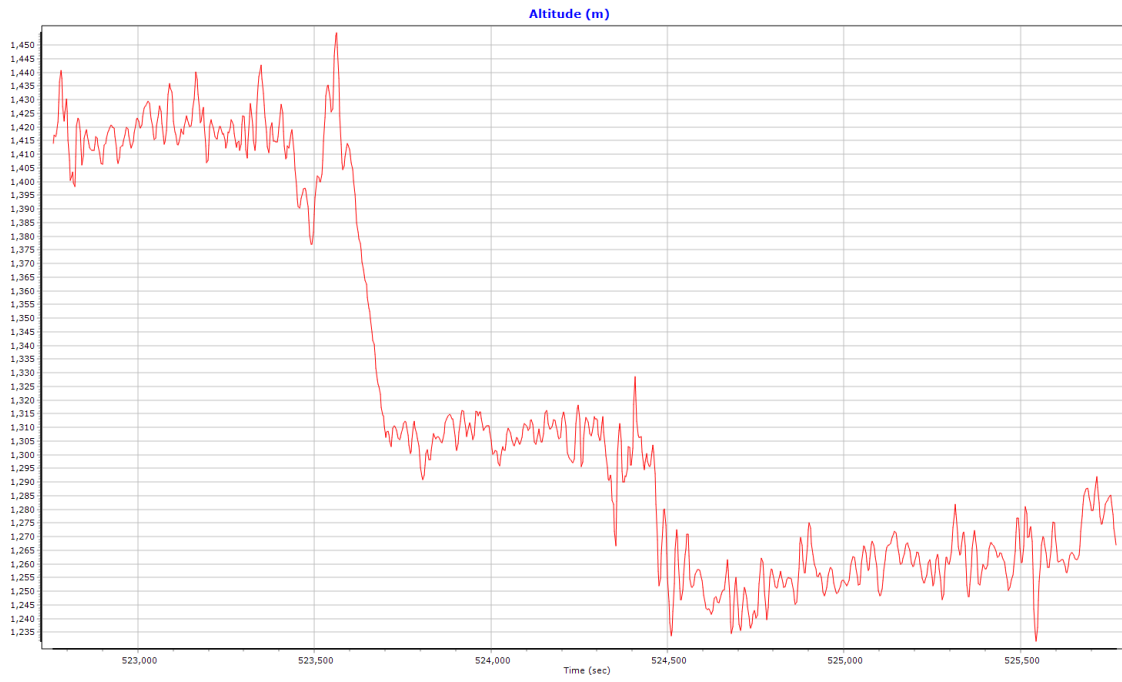


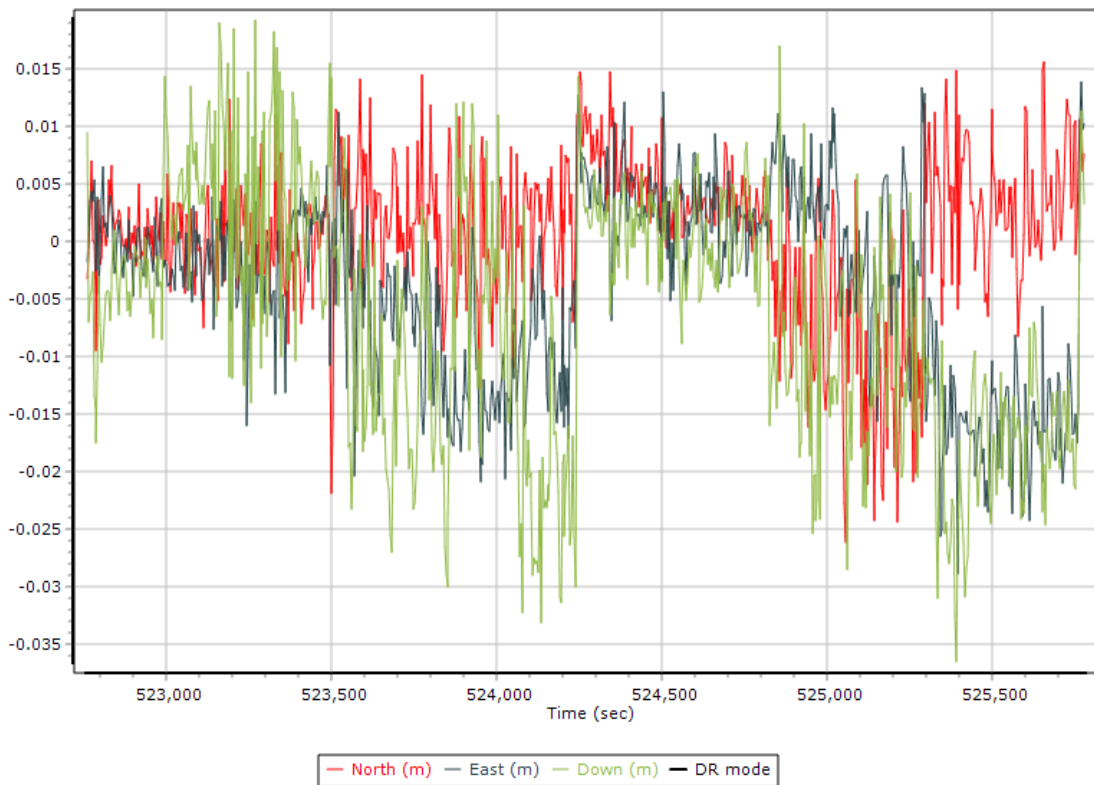
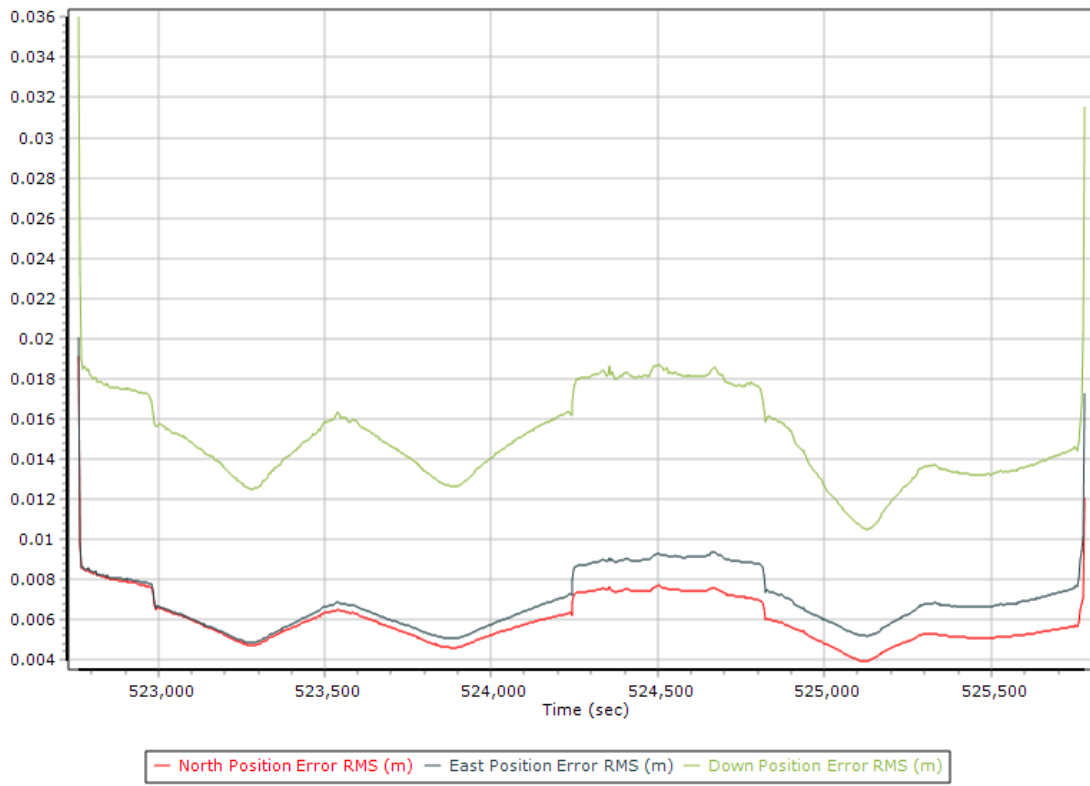


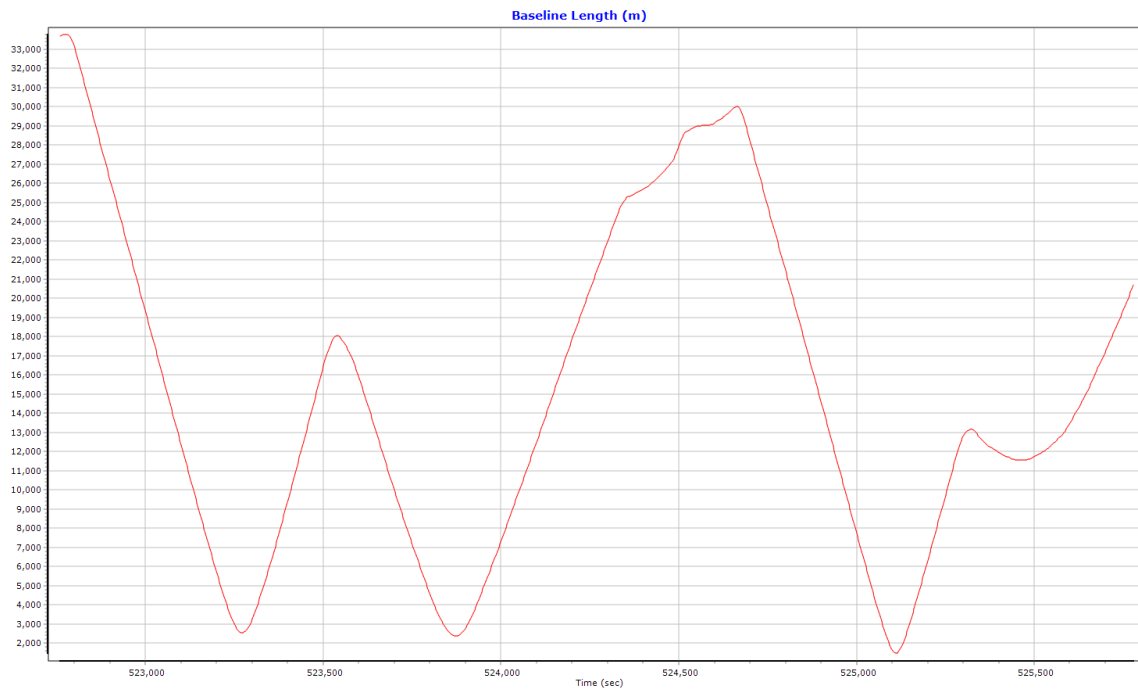
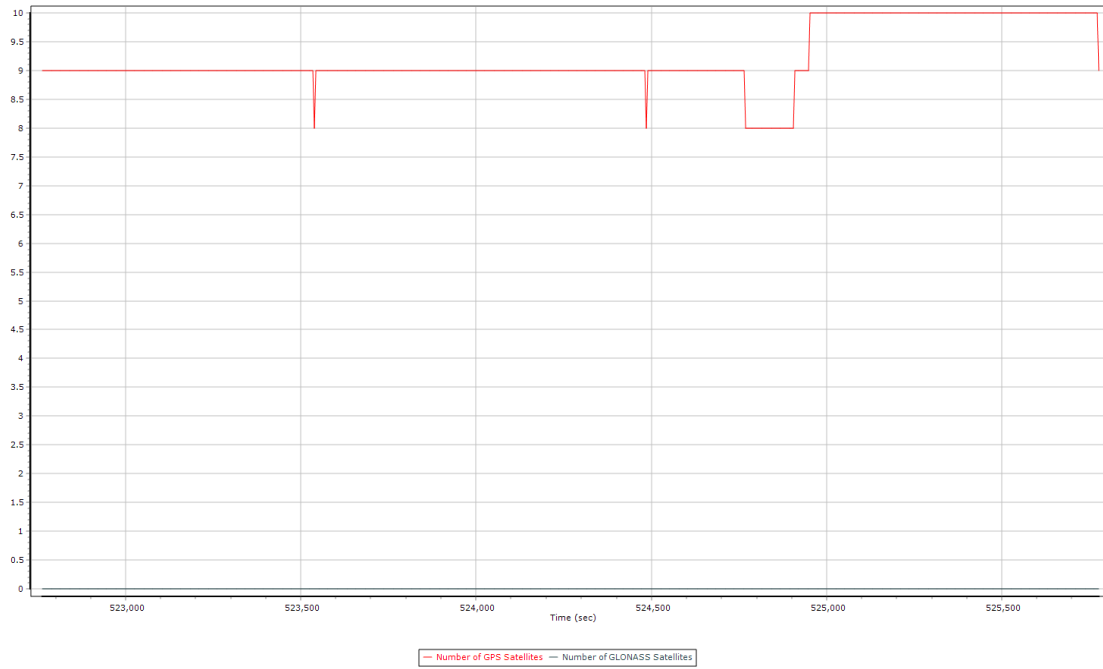
AZT18145B2

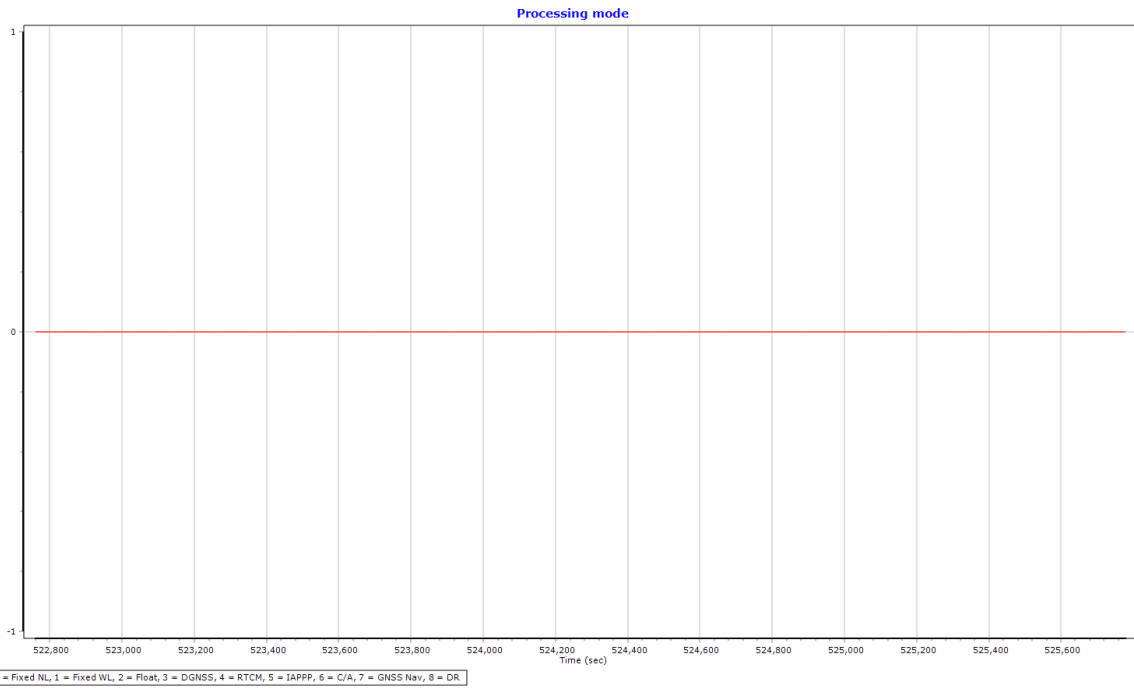
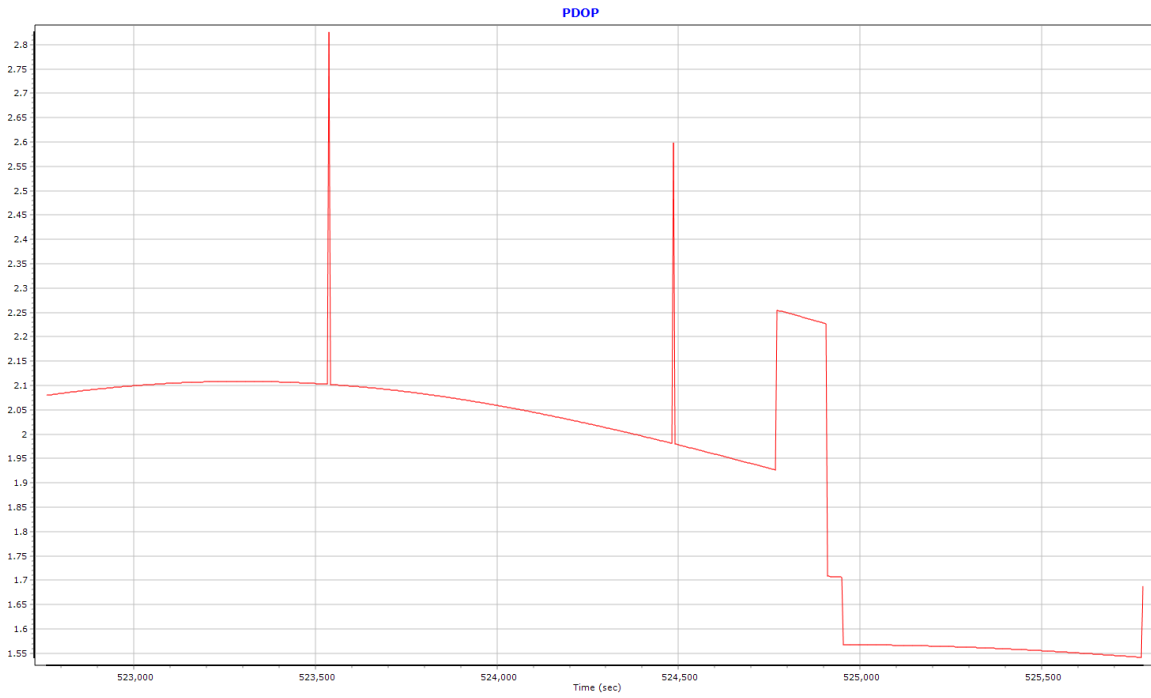




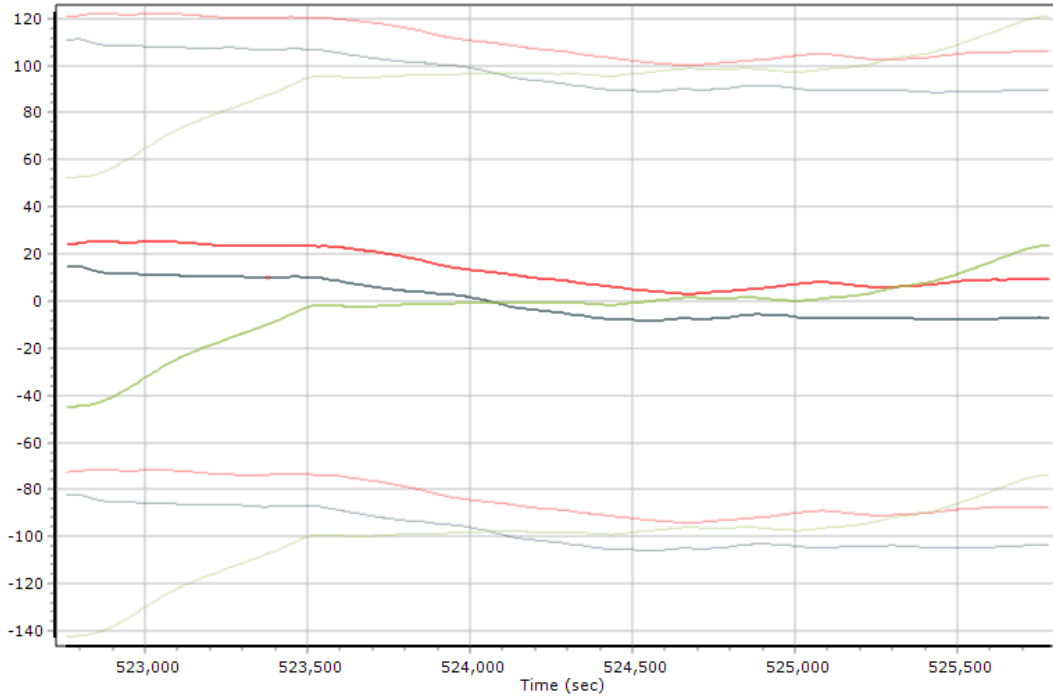




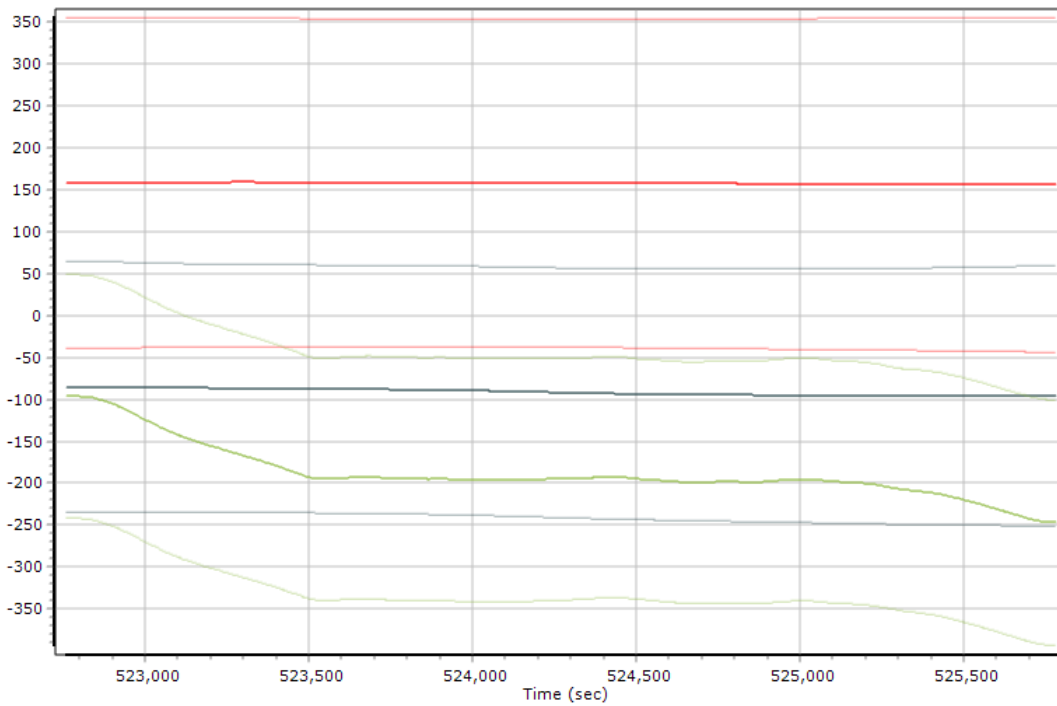




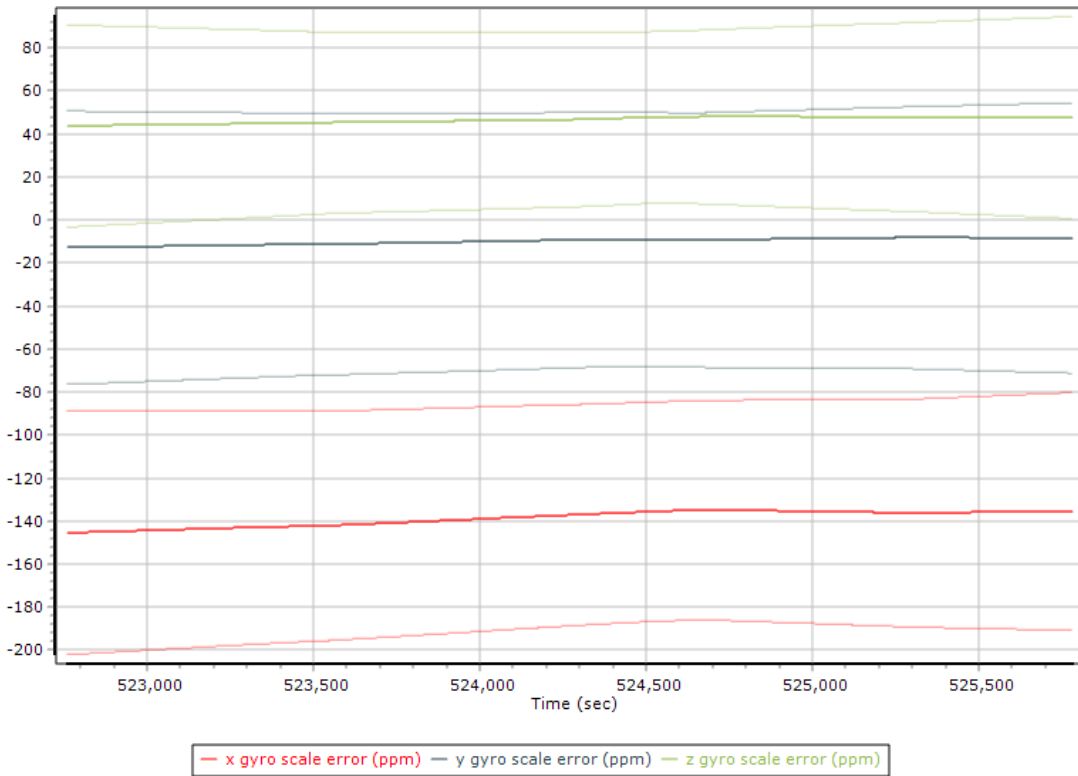
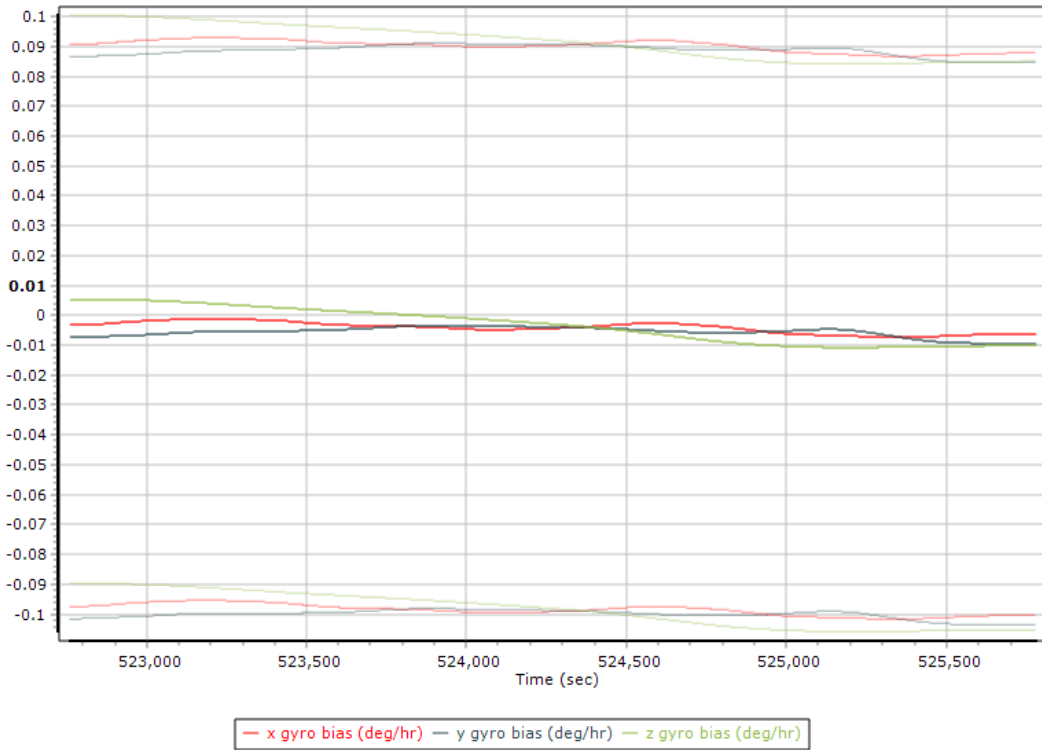
Sensor Errors



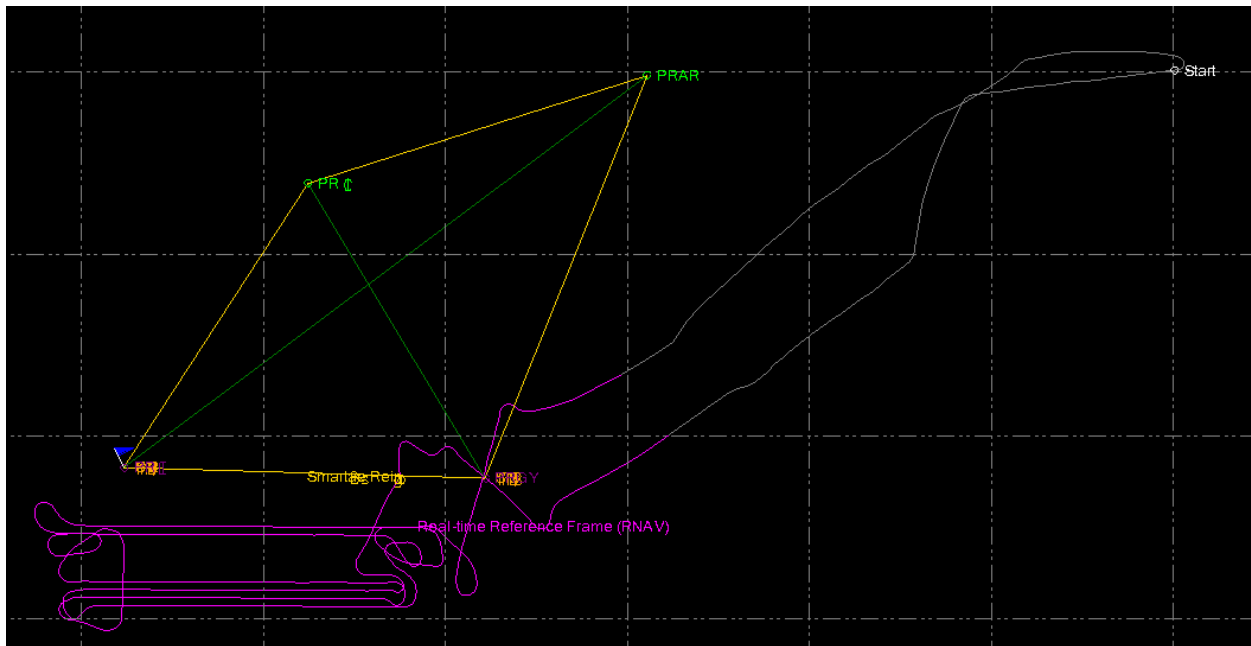
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)



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



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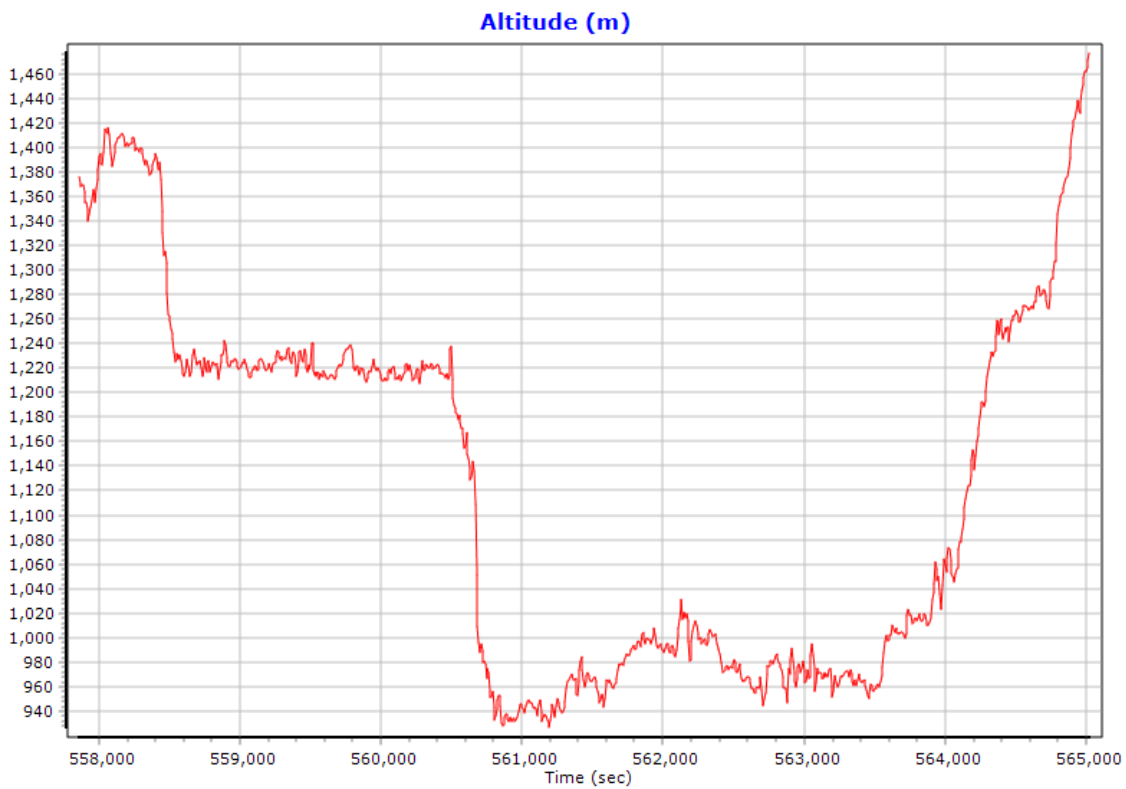
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000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

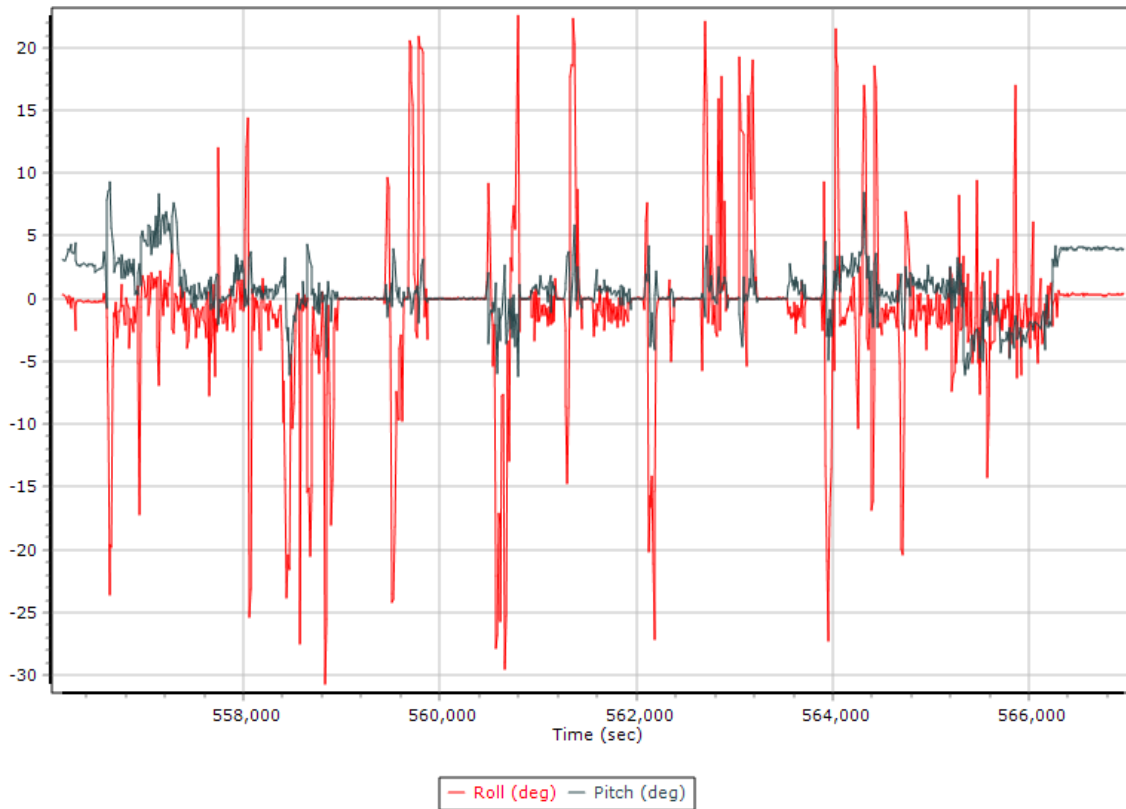
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

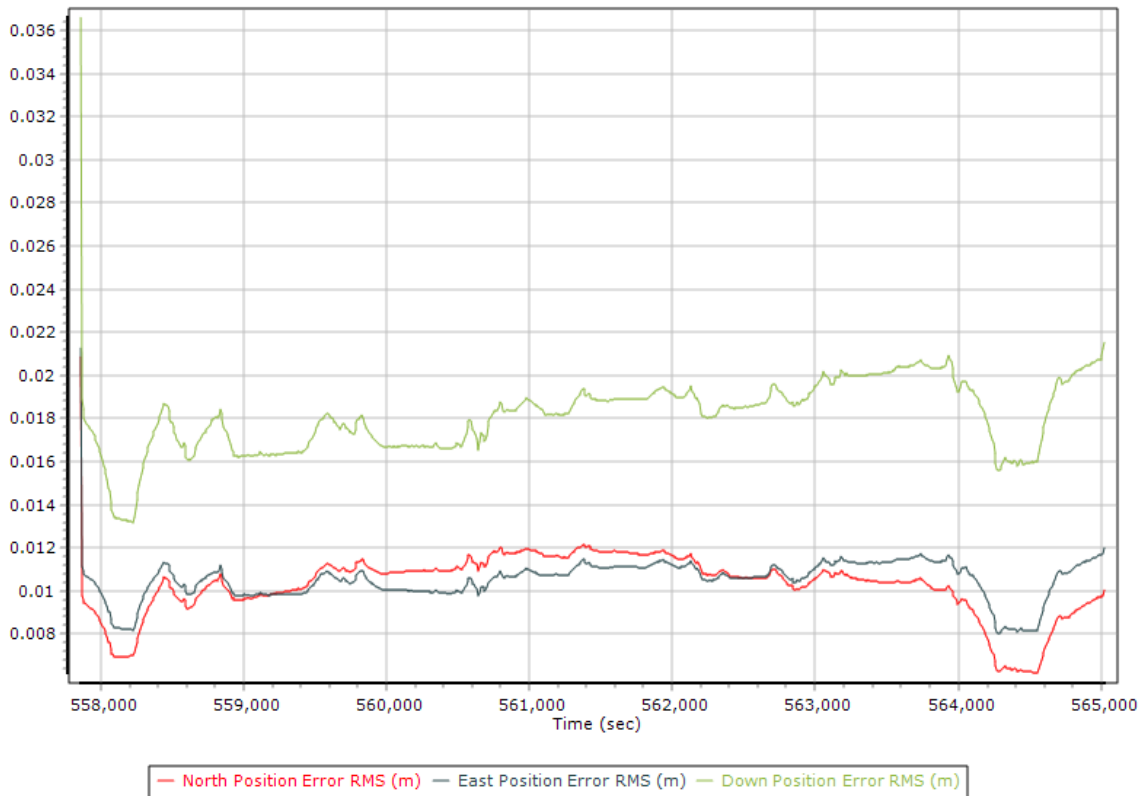
Timing

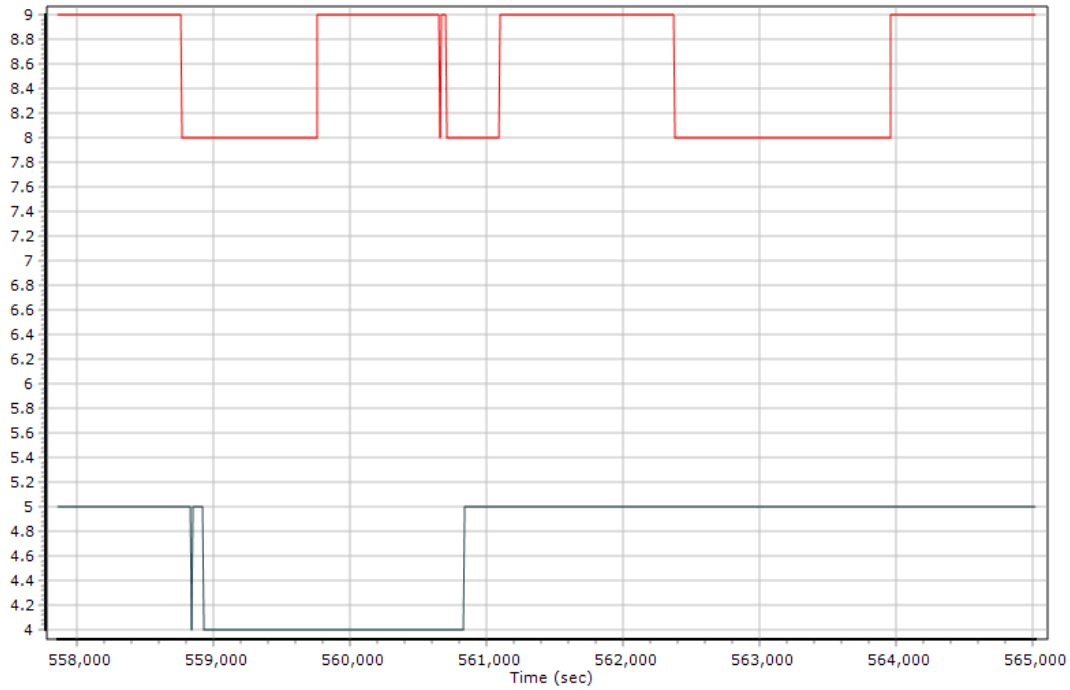
Start	557860.000	Data	Incr. (sec)	^
End	565033.000	Output Record	0.005000	
<input type="checkbox"/> Entire time interval		IMU	0.005000	
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000	v

UTC Offset 18.000



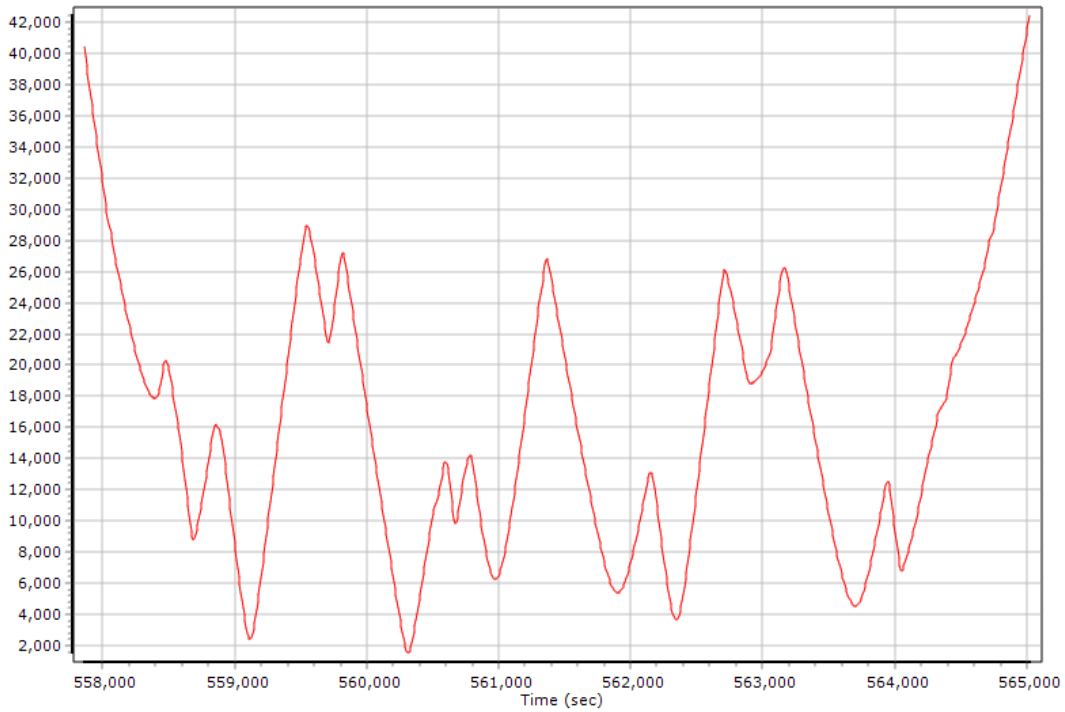


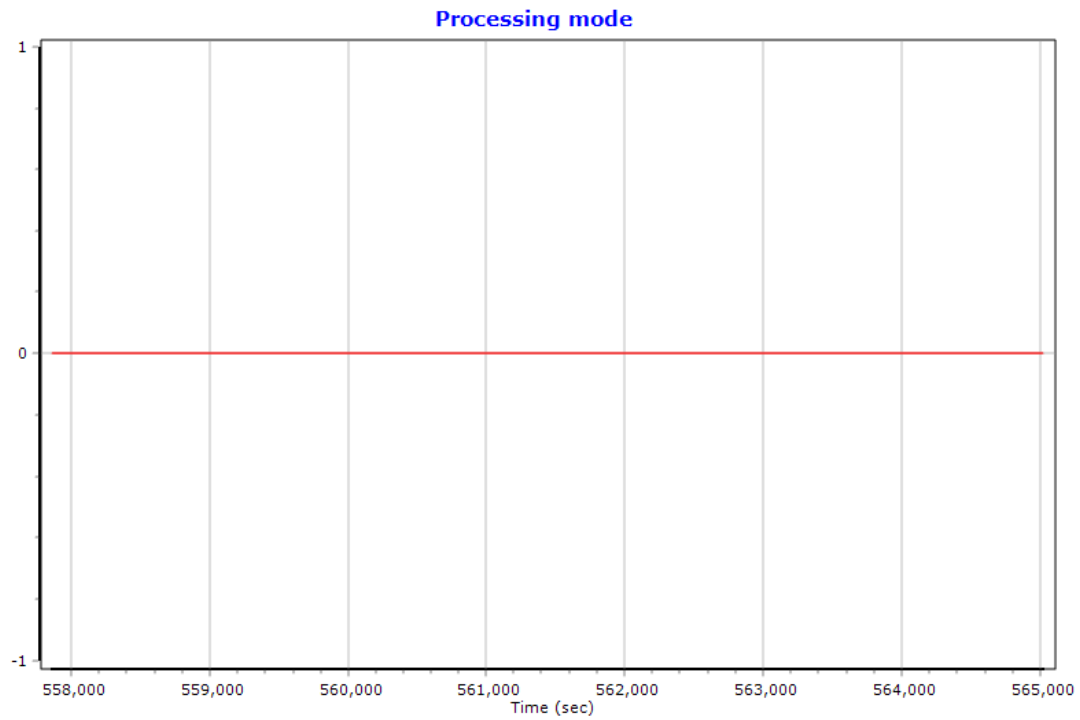
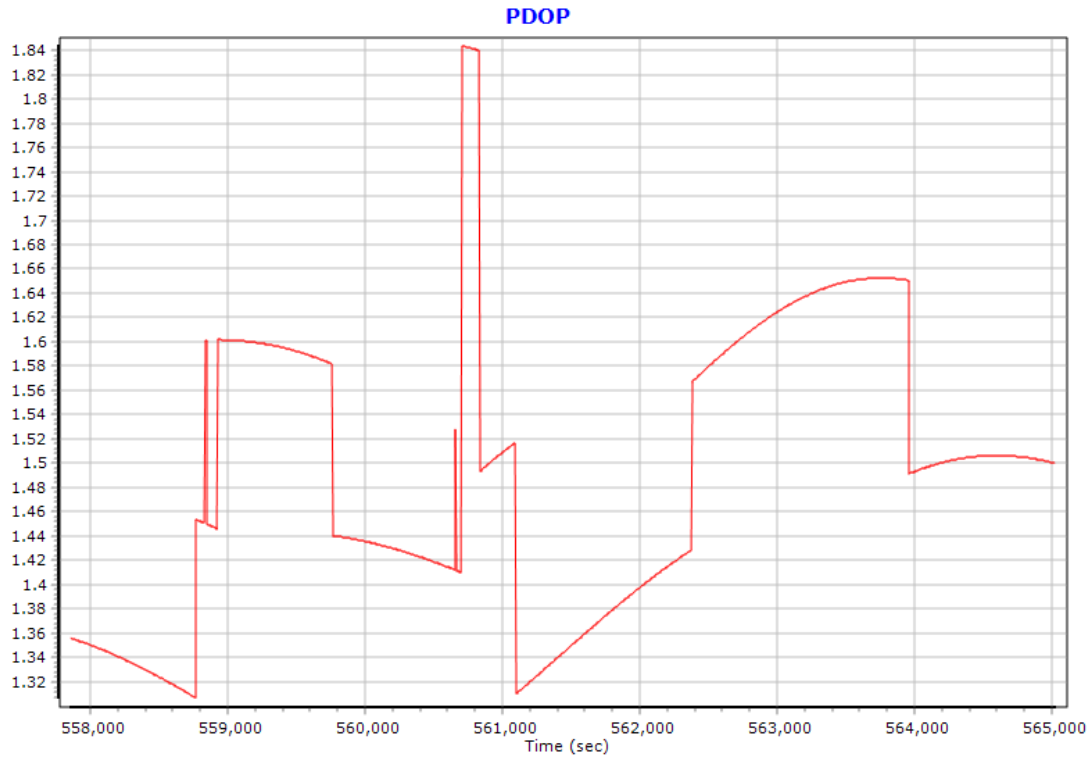




— Number of GPS Satellites — Number of GLONASS Satellites

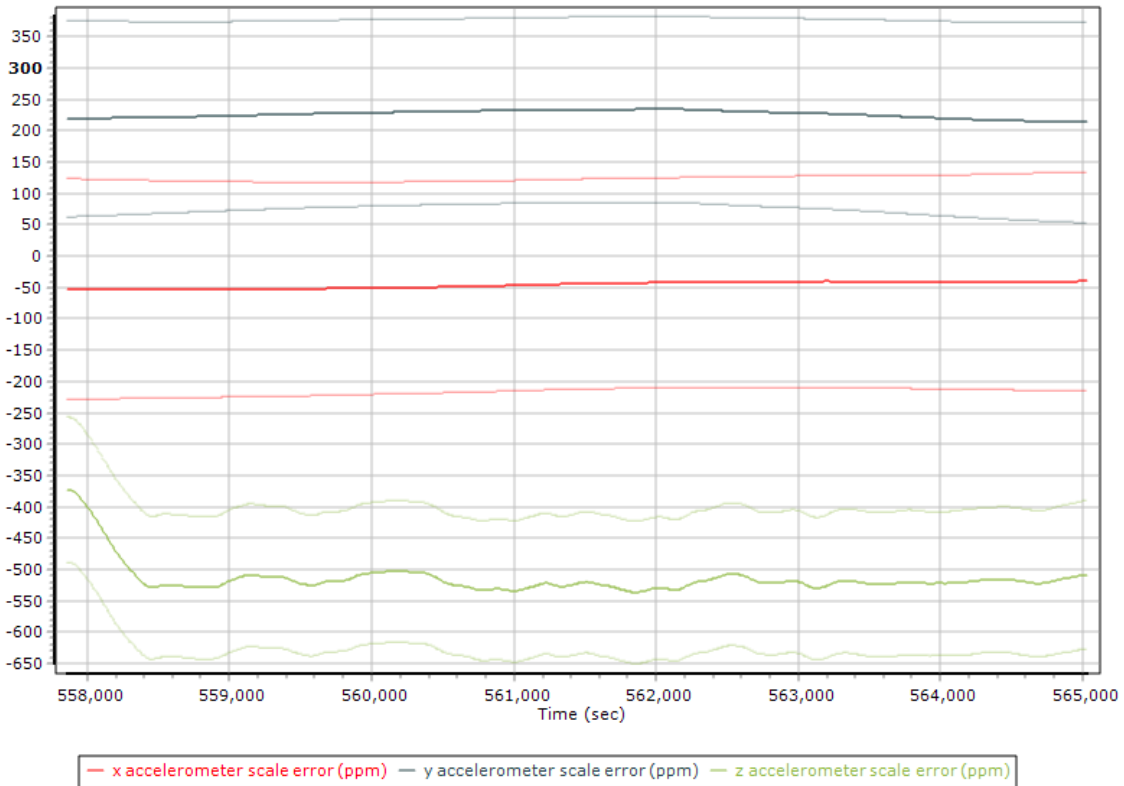
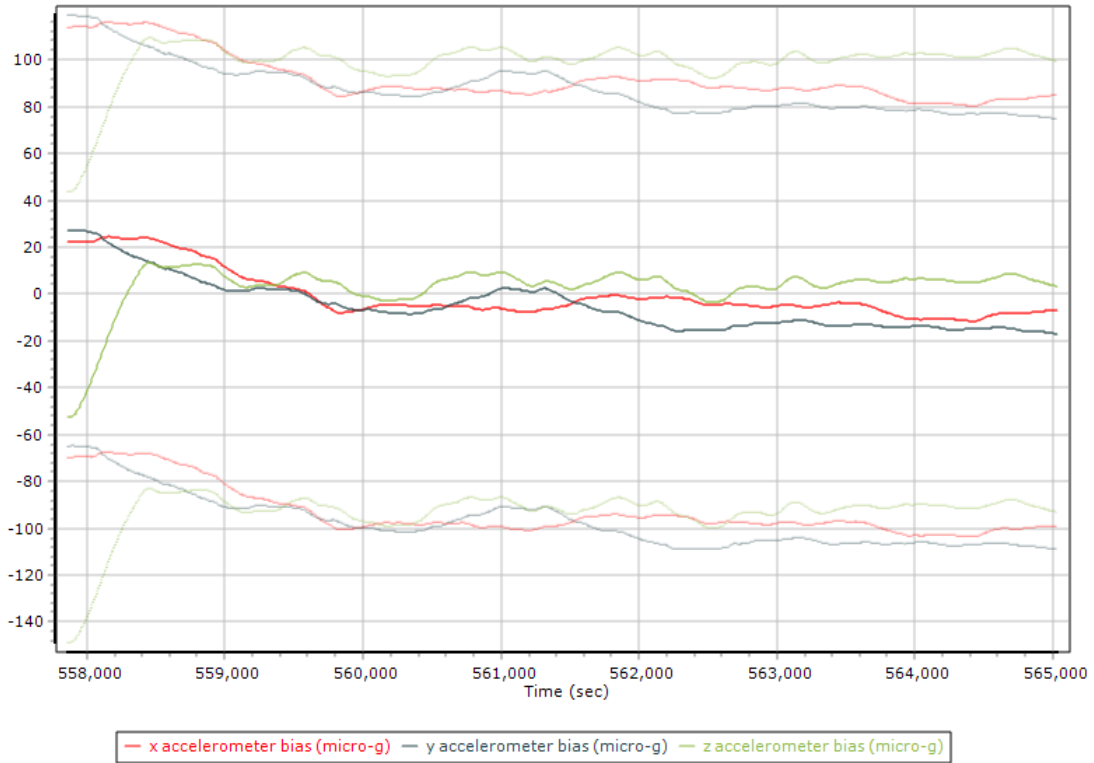
Baseline Length (m)

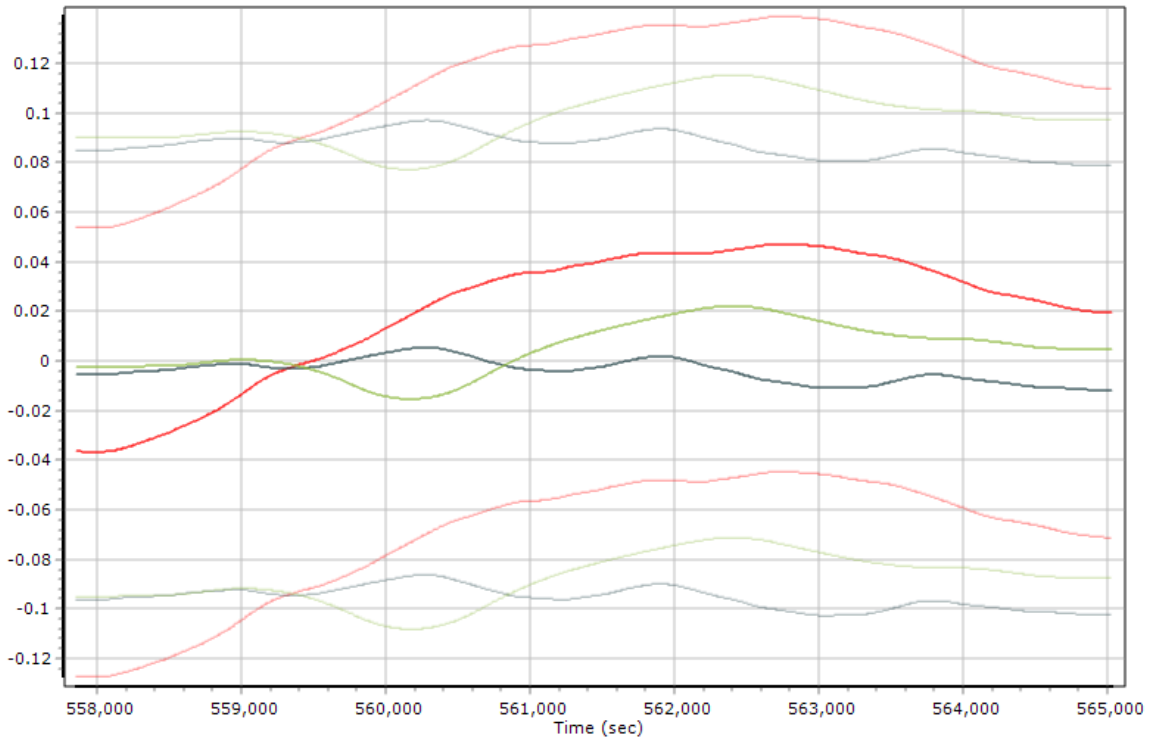




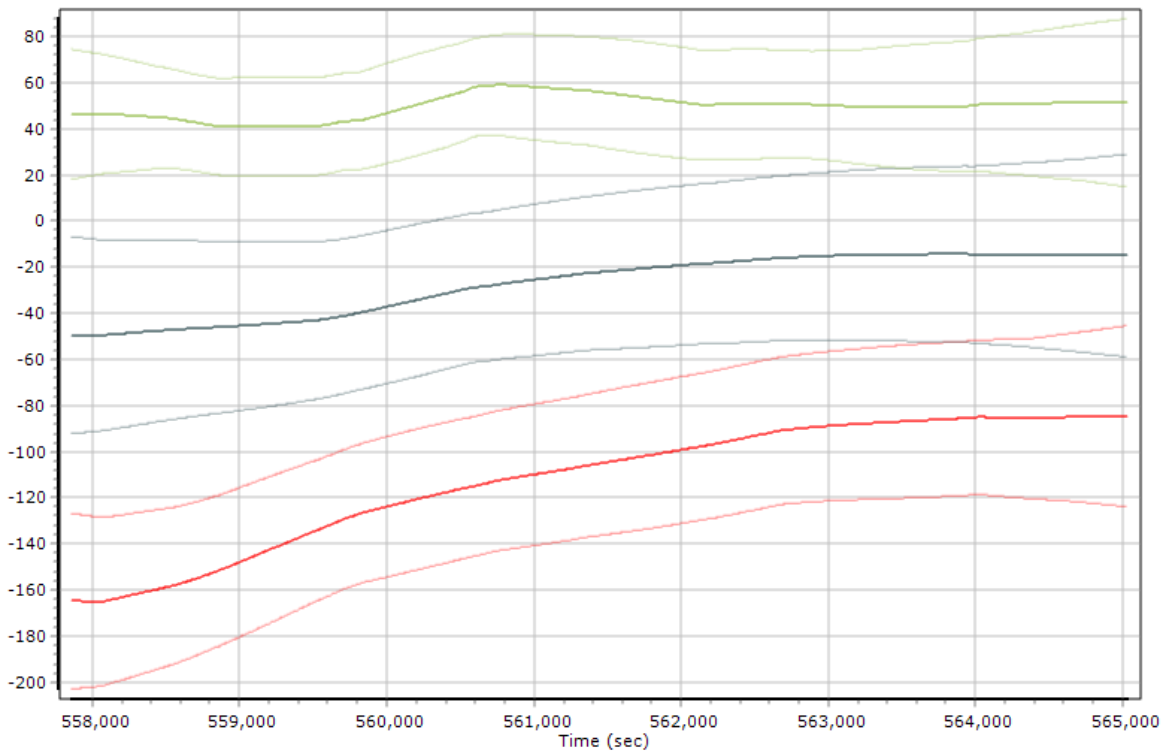
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors



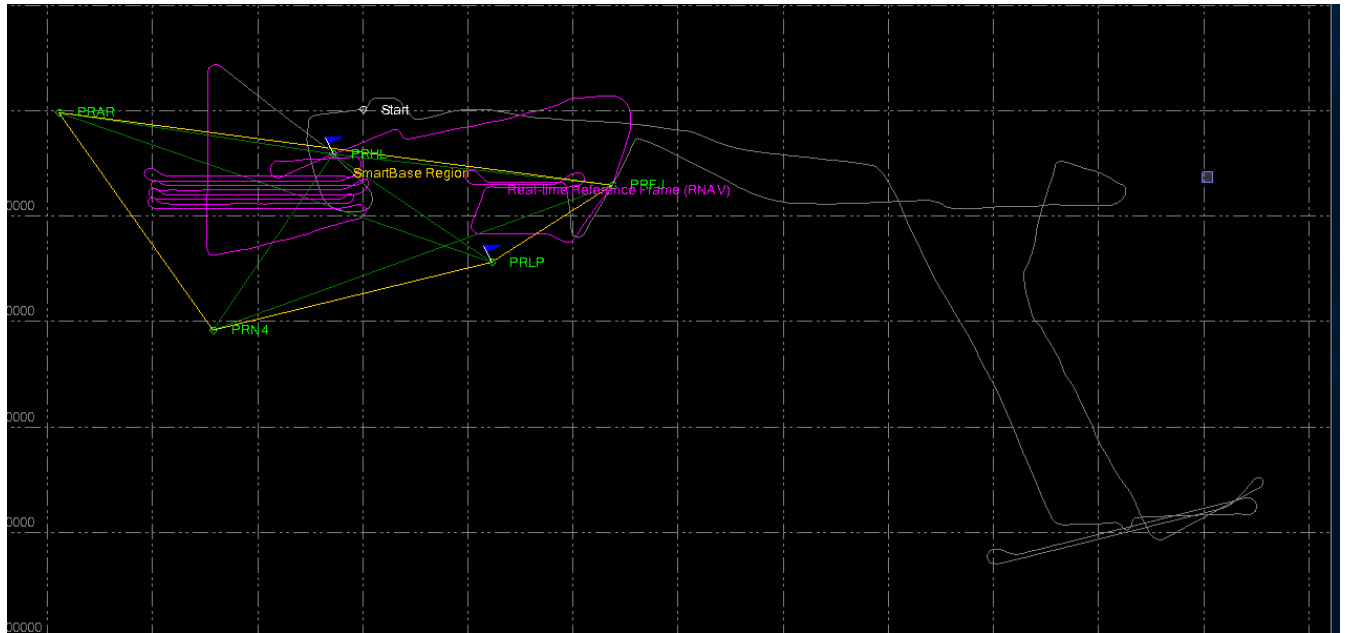


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



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

AZT18146B



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="0.25"/>			
<3cm 10cm 50cm 1m 10m			

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

Timing

Start

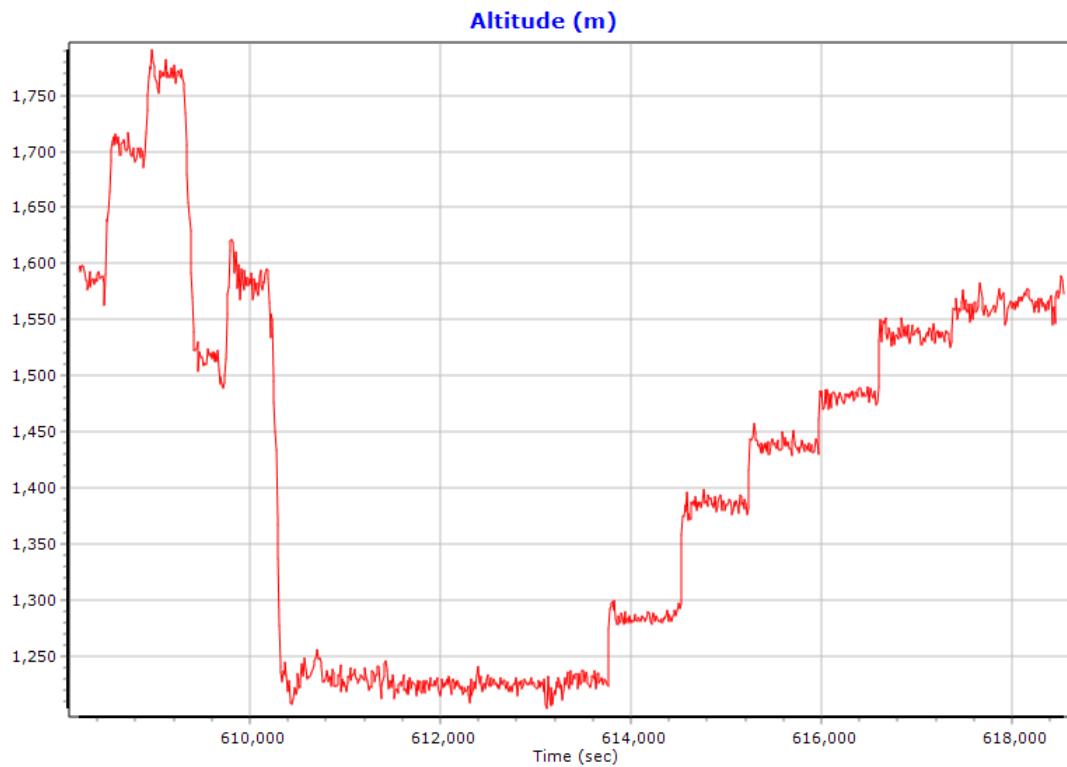
End

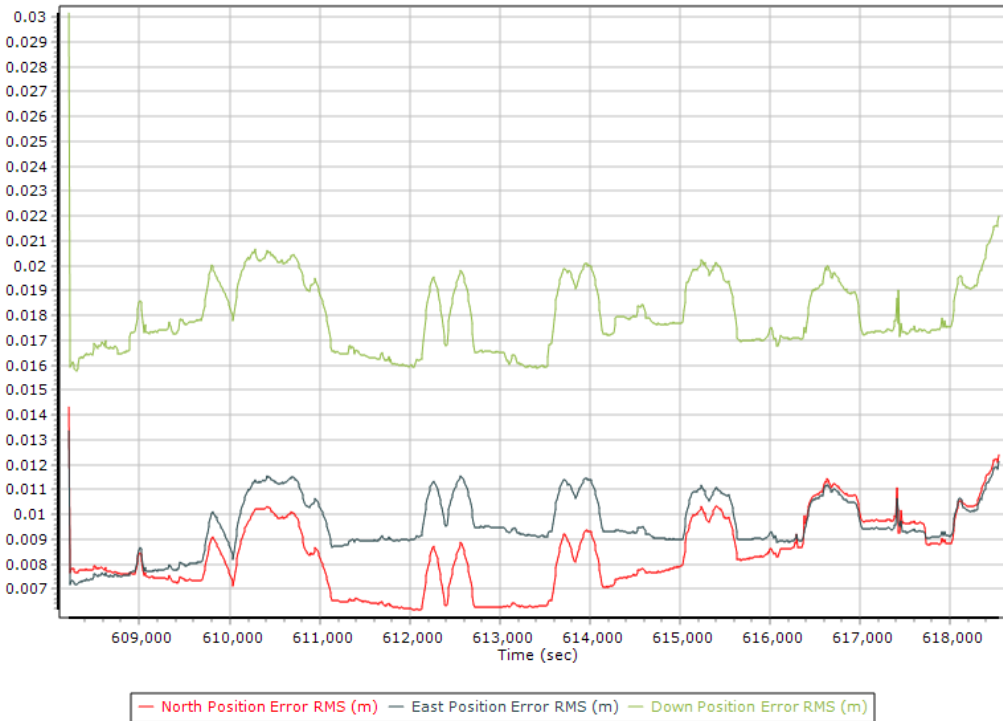
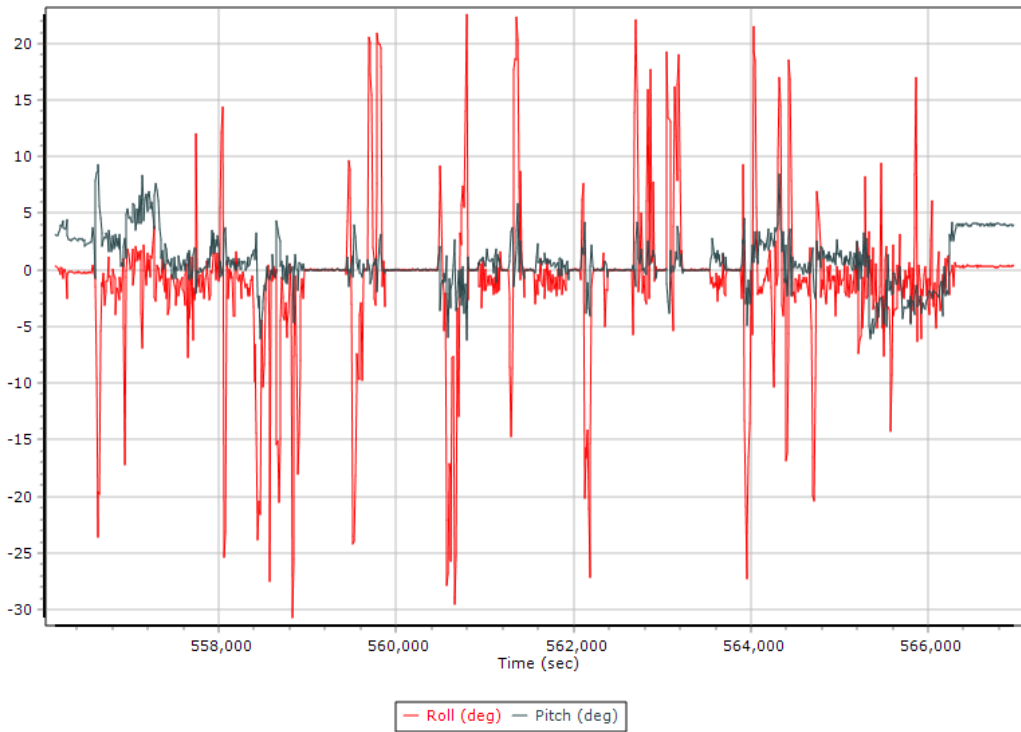
Entire time interval

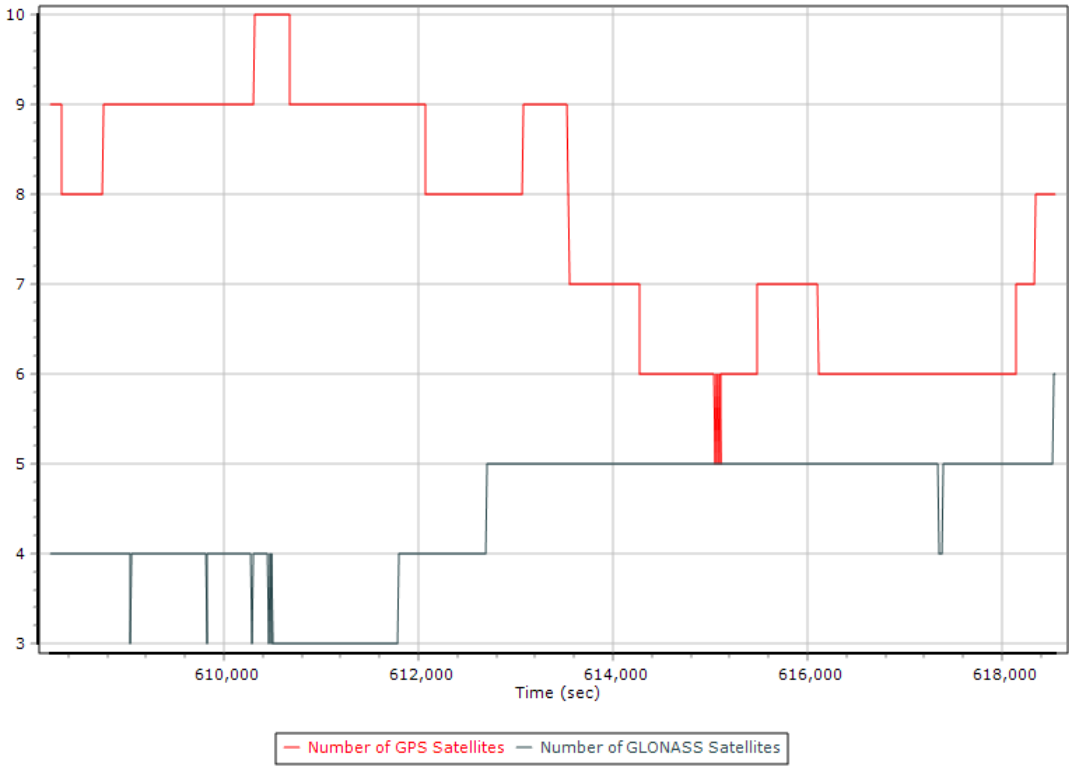
Seconds of start week

UTC Offset

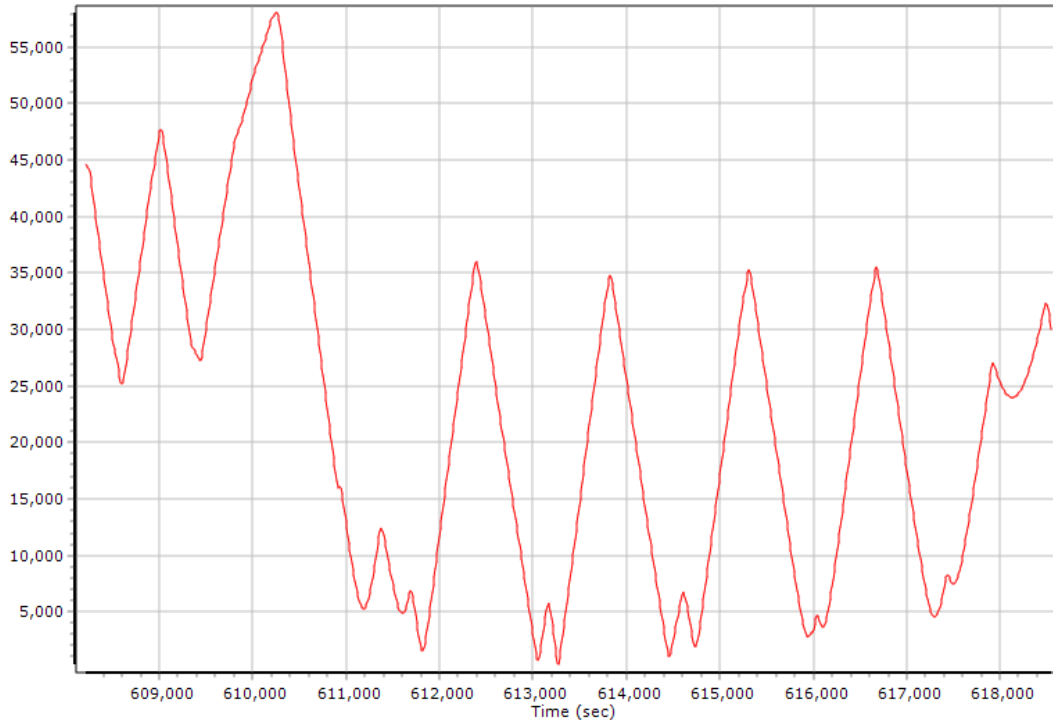
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



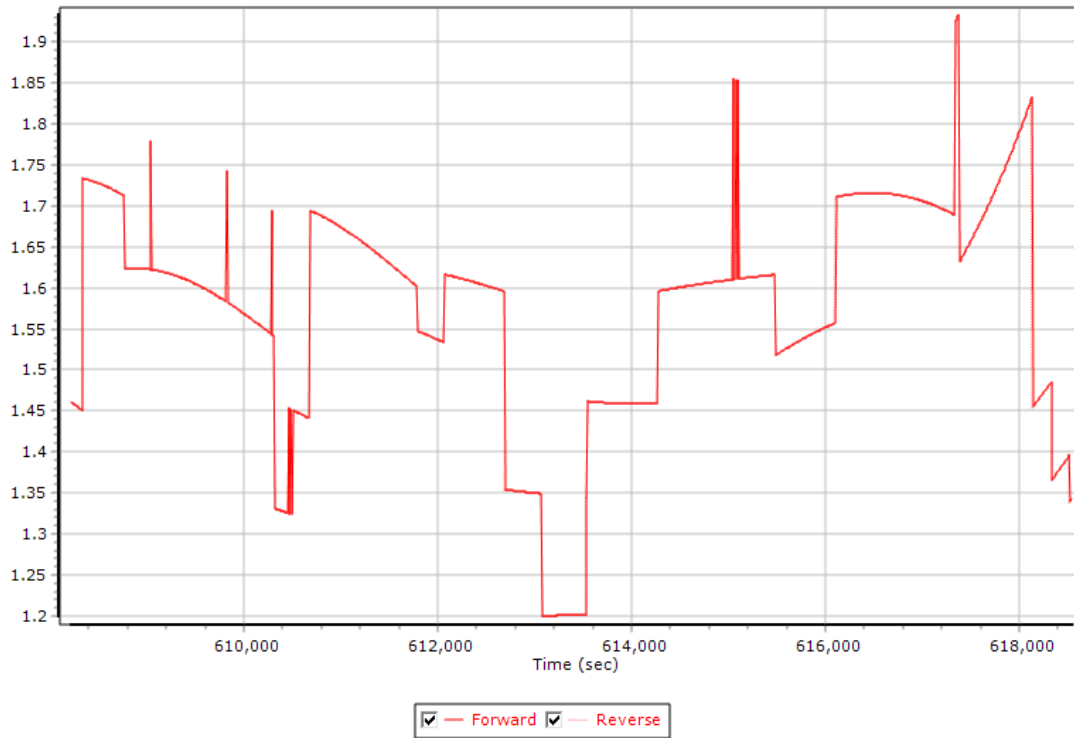




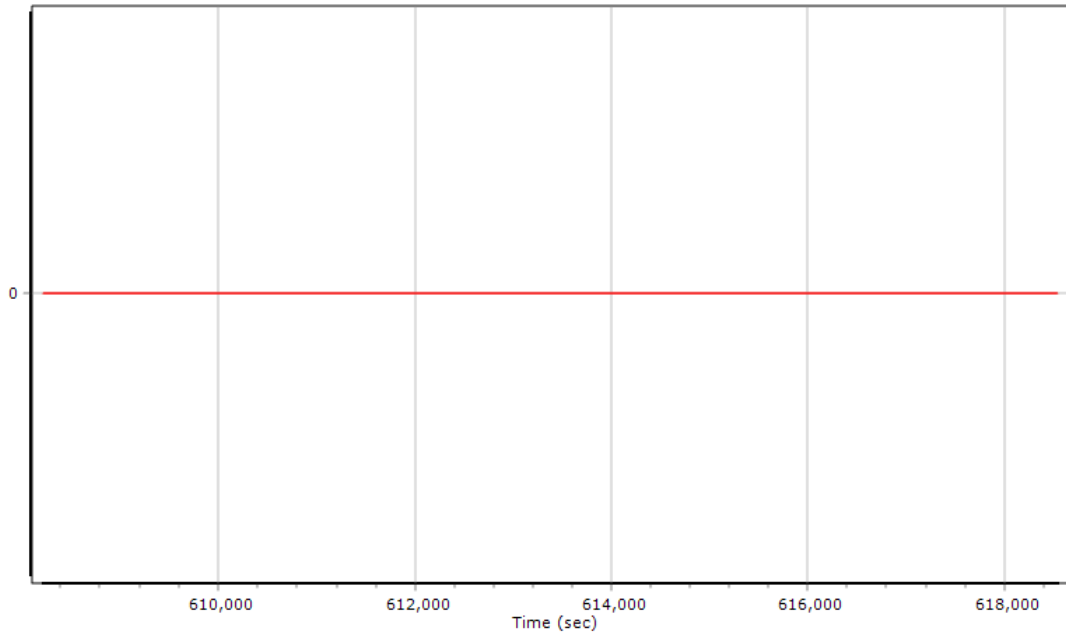
Baseline Length(m)



PDOP

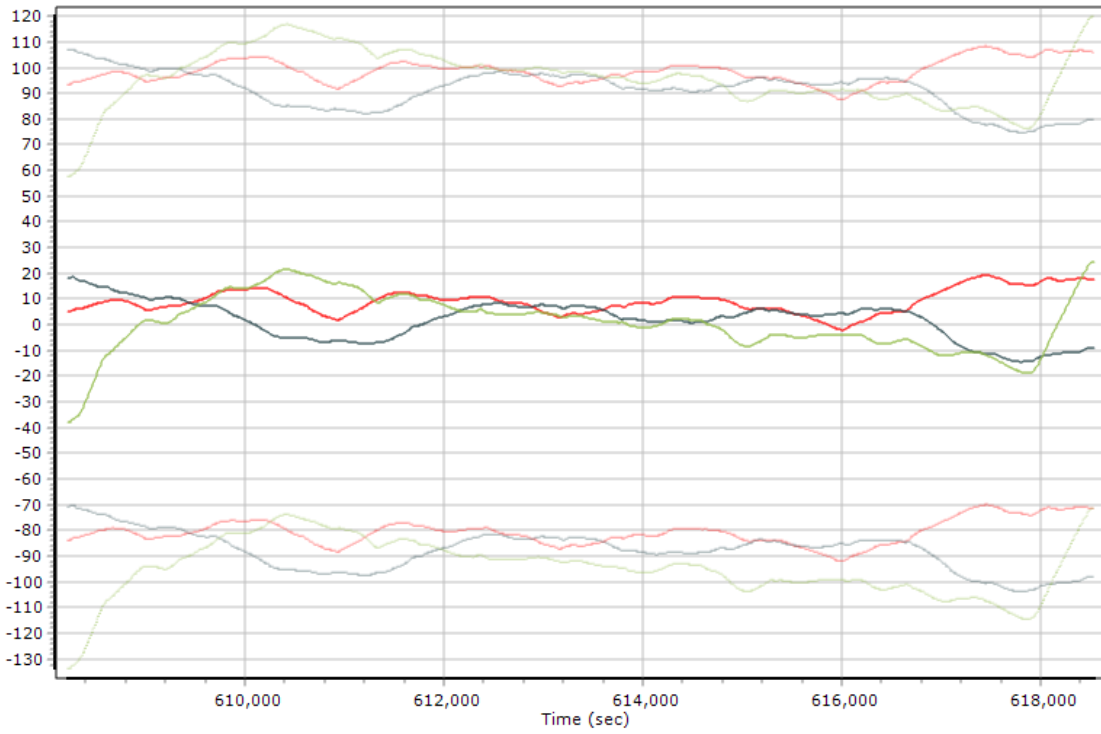


Processing Mode

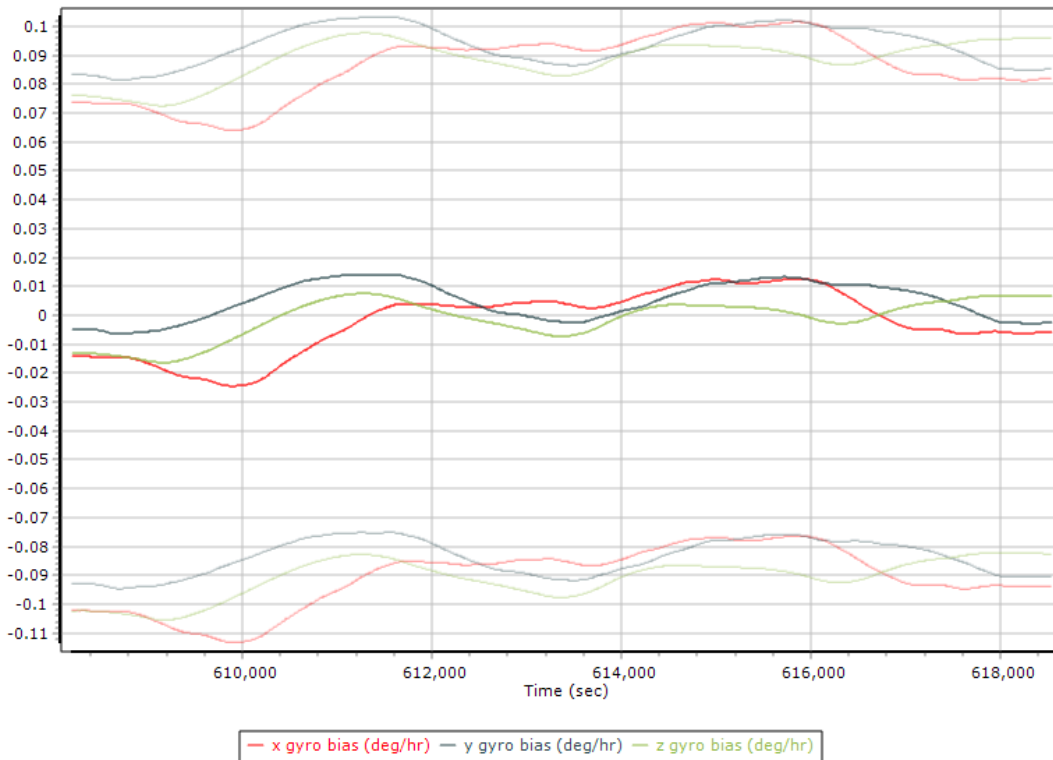
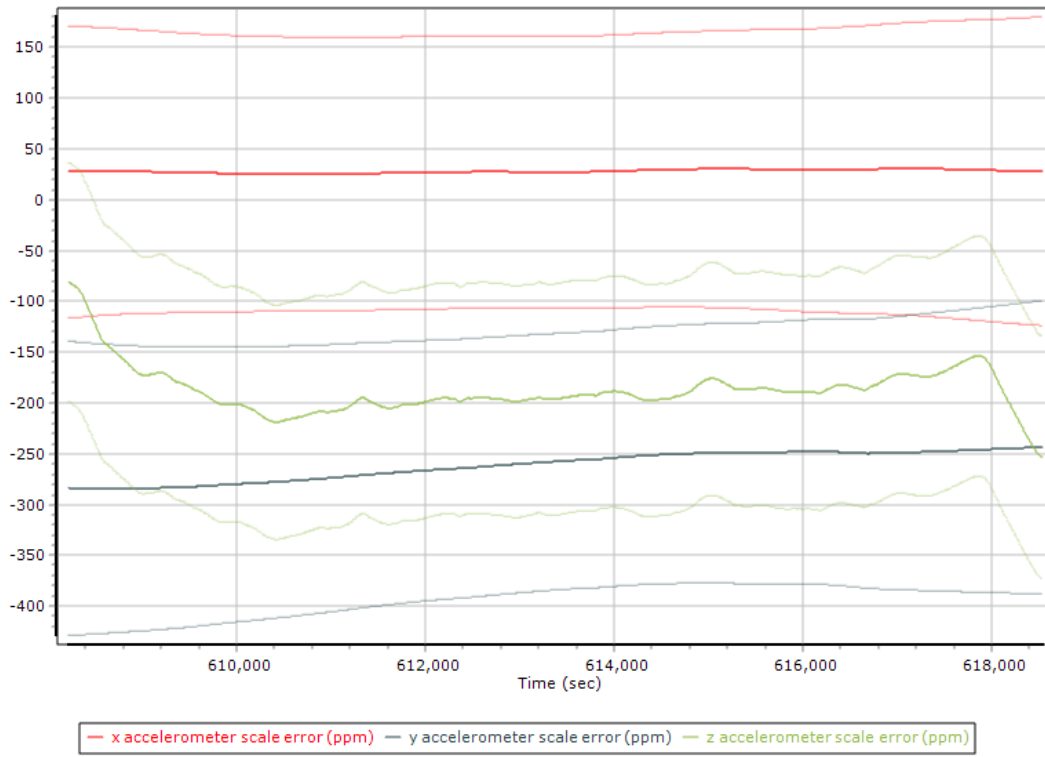


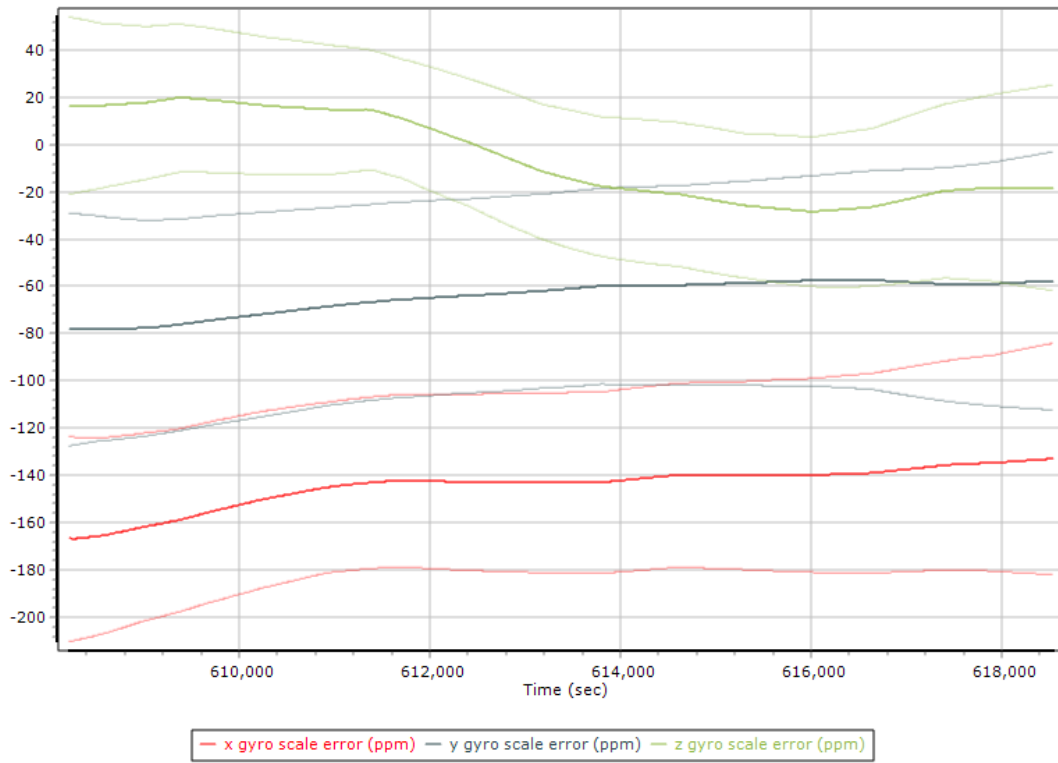
Forward Reverse

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

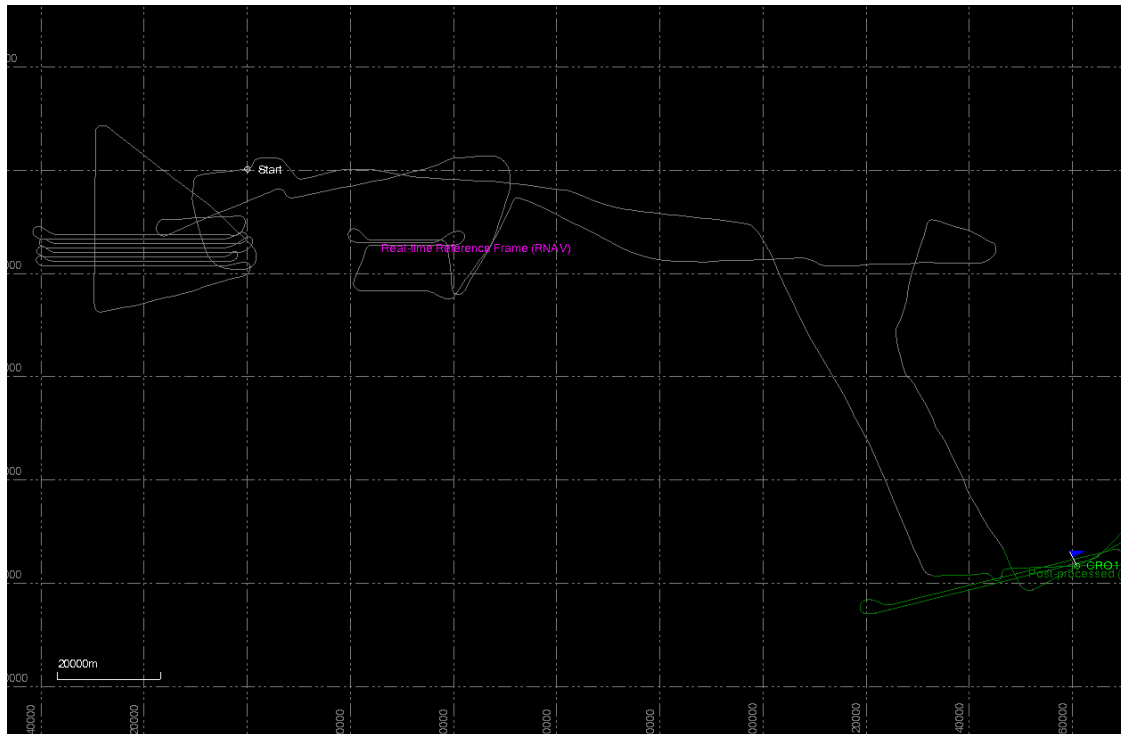


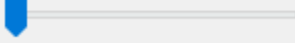
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)






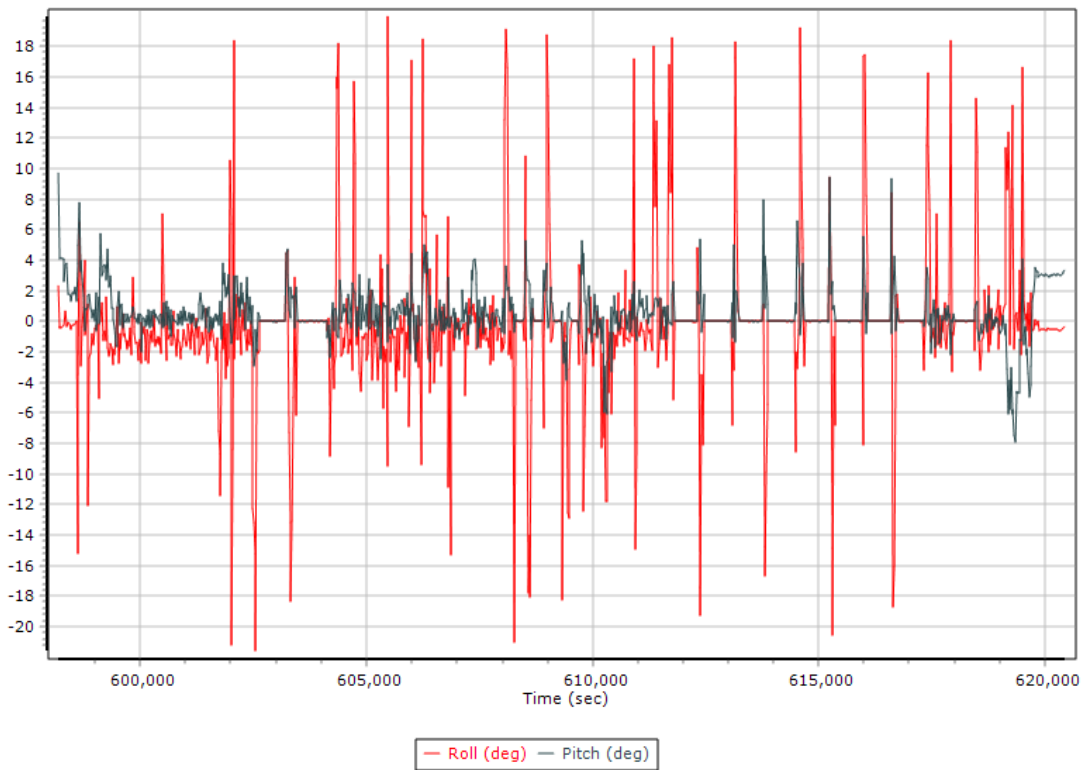
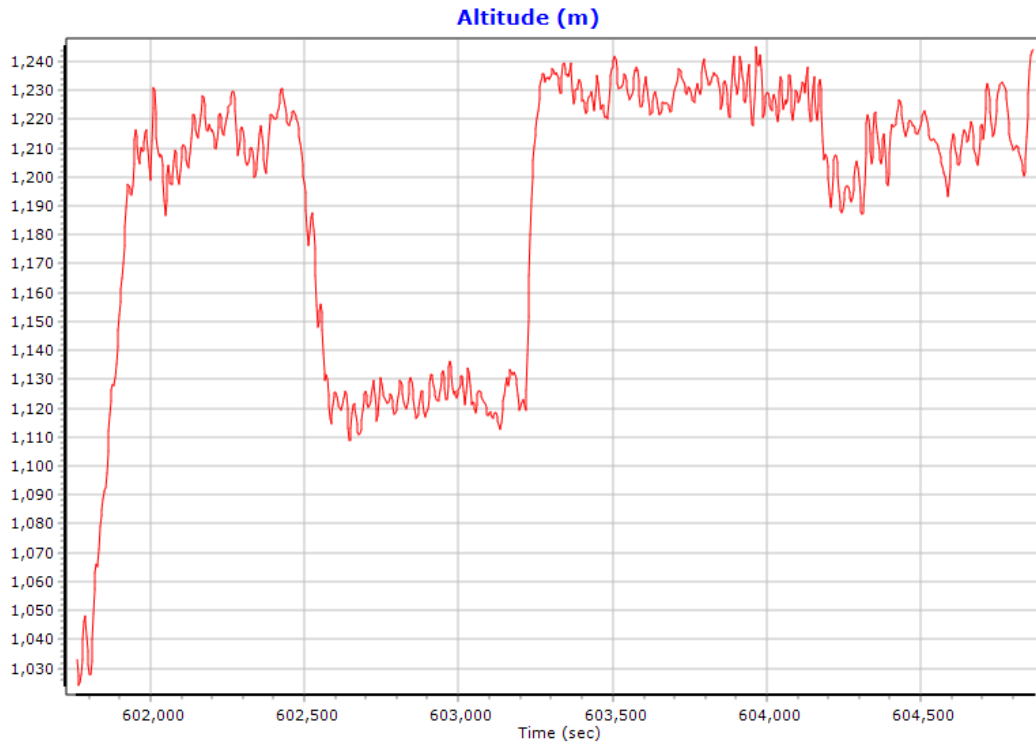
AZT18146B2

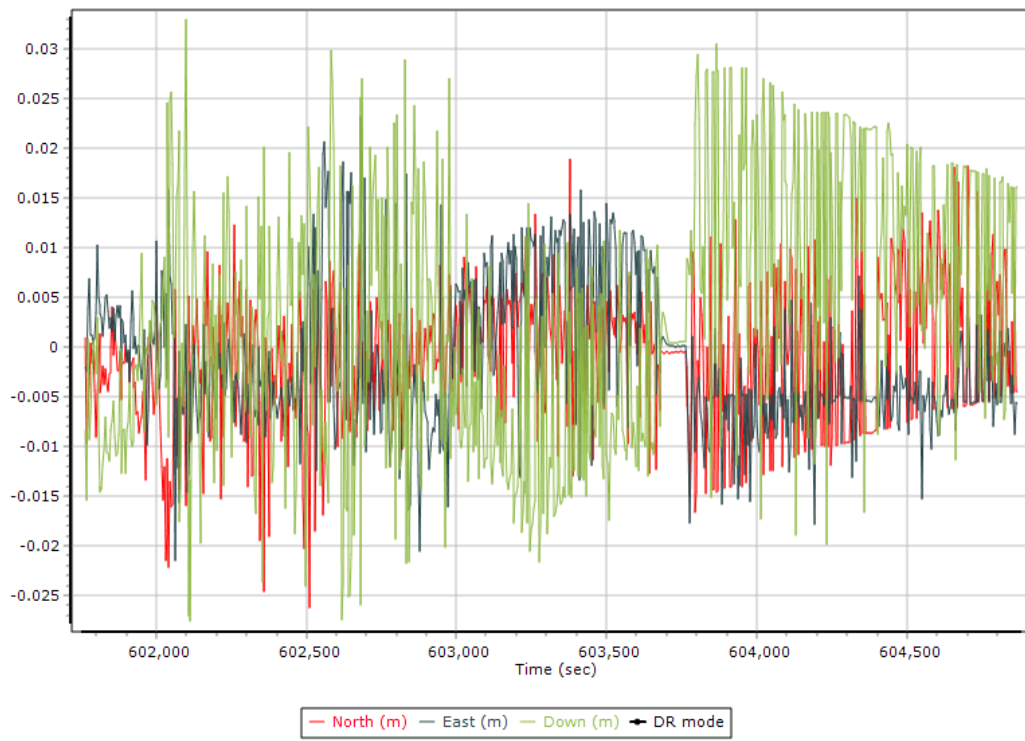
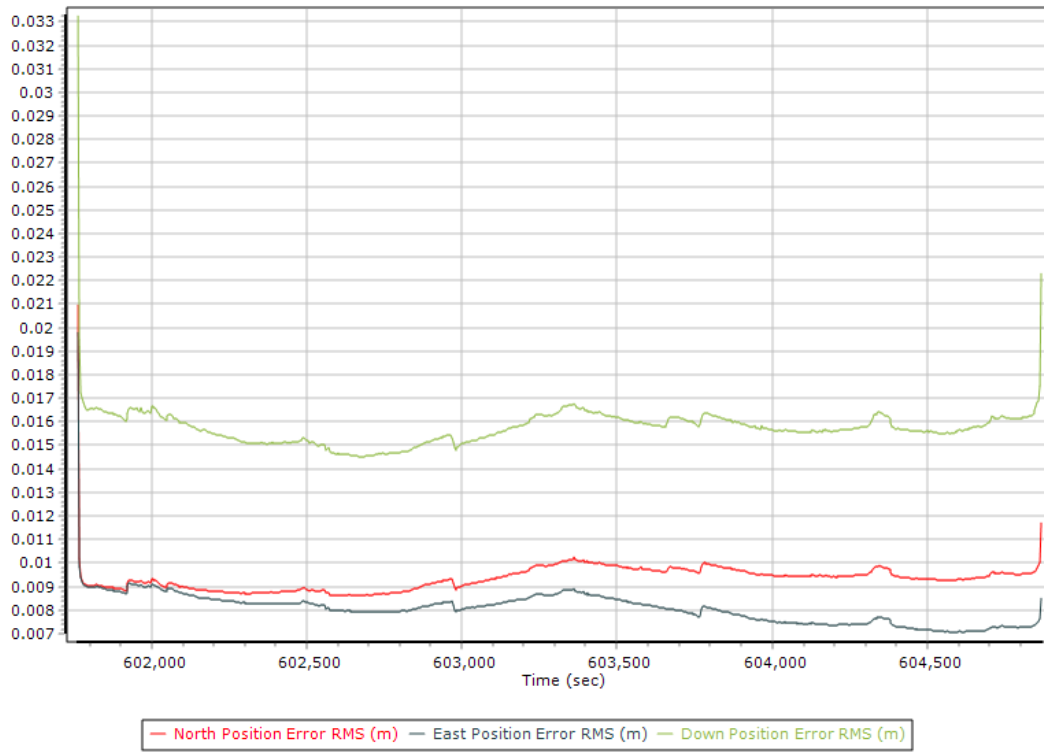


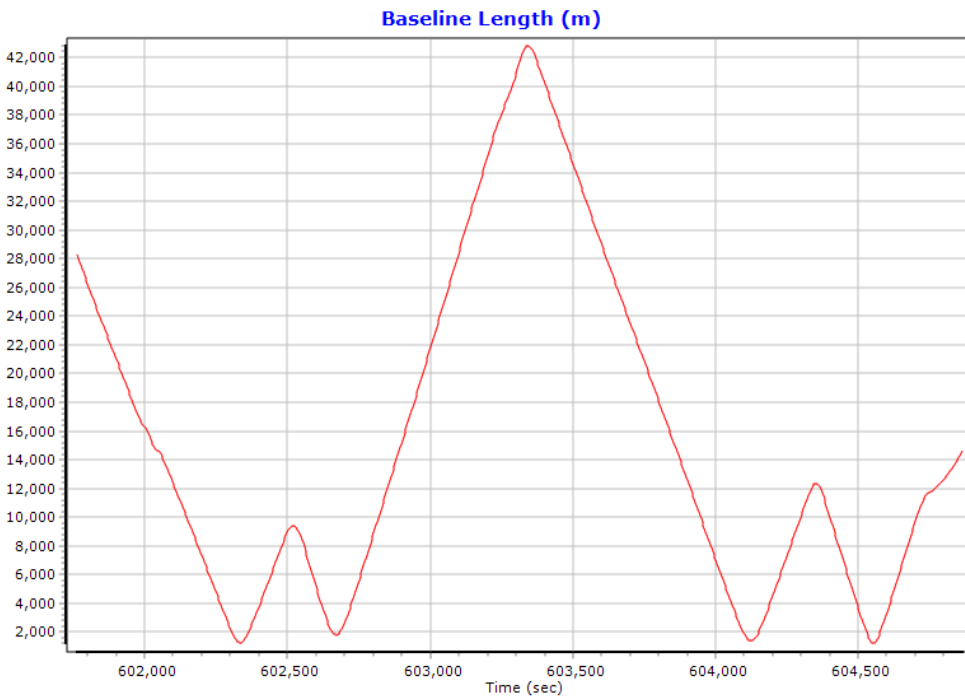
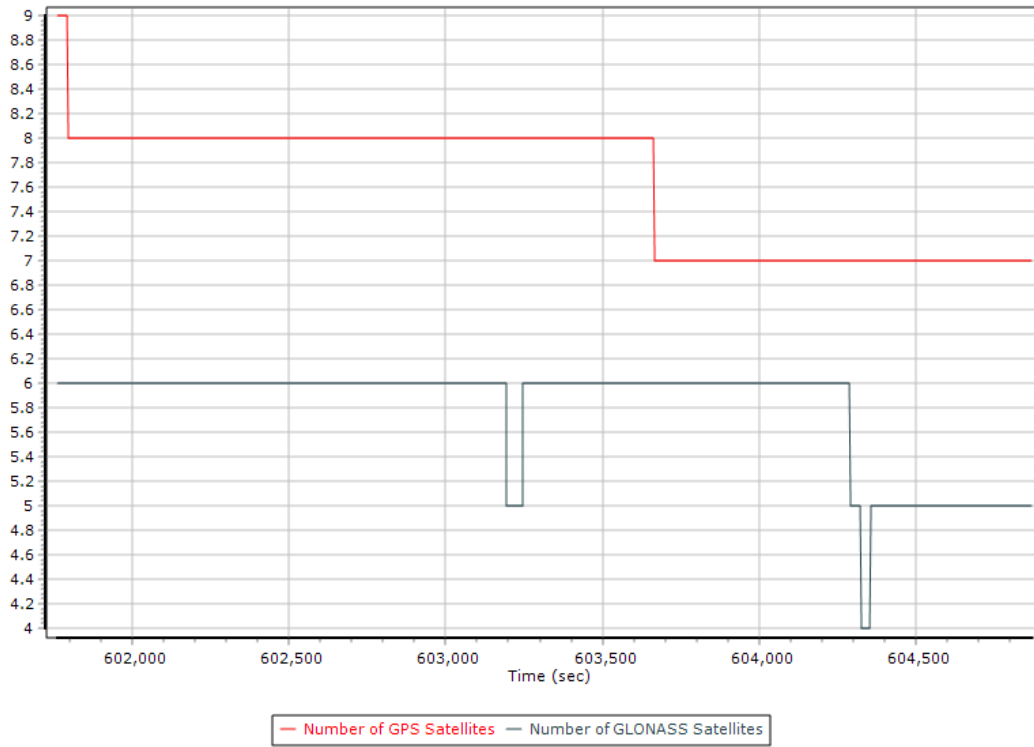
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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			
	<3cm 10cm 50cm 1m 10m		

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

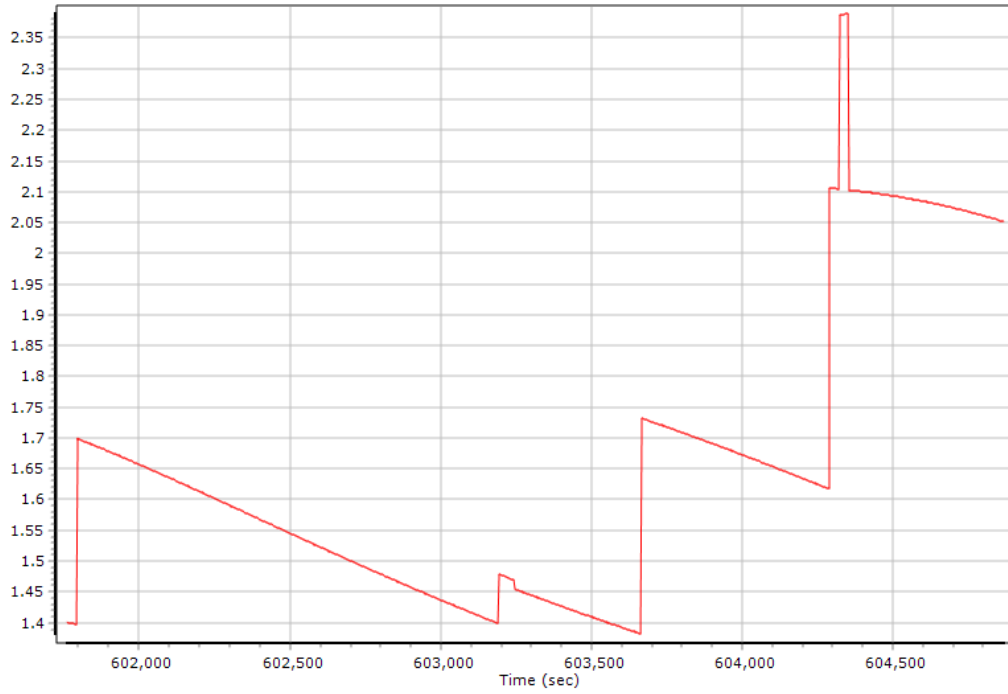
Timing									
Start	<input type="text" value="601760.037"/>								
End	<input type="text" value="604870.762"/>								
<input type="checkbox"/> Entire time interval									
<input checked="" type="checkbox"/> Seconds of start week									
UTC Offset	<input type="text" value="18.000"/>								
<table border="1"><thead><tr><th>Data</th><th>Incr. (sec)</th></tr></thead><tbody><tr><td>Output Record</td><td>0.005000</td></tr><tr><td>IMU</td><td>0.005000</td></tr><tr><td>Primary GNSS</td><td>1.000000</td></tr></tbody></table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000	
Data	Incr. (sec)								
Output Record	0.005000								
IMU	0.005000								
Primary GNSS	1.000000								



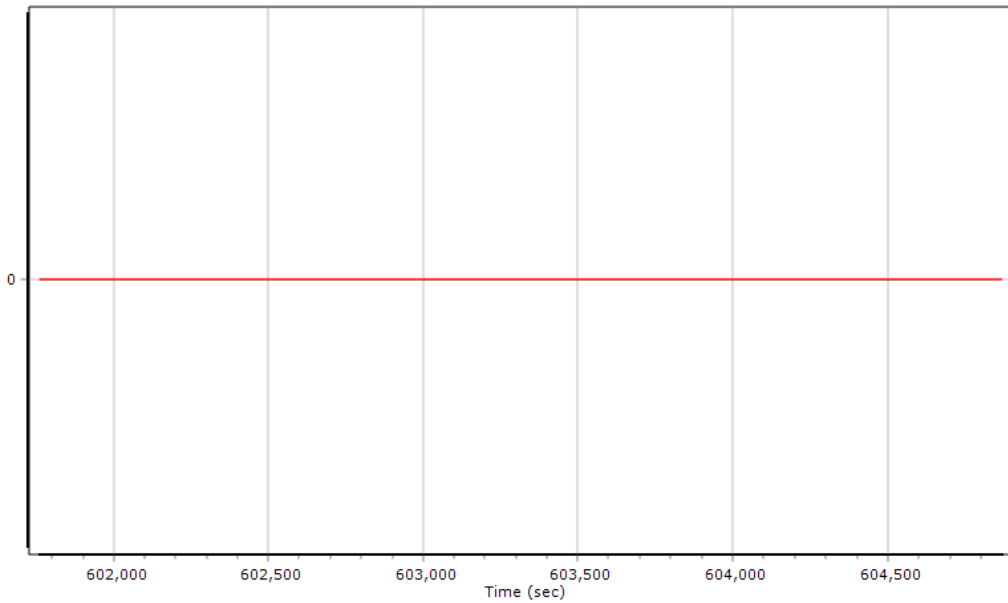




PDOP



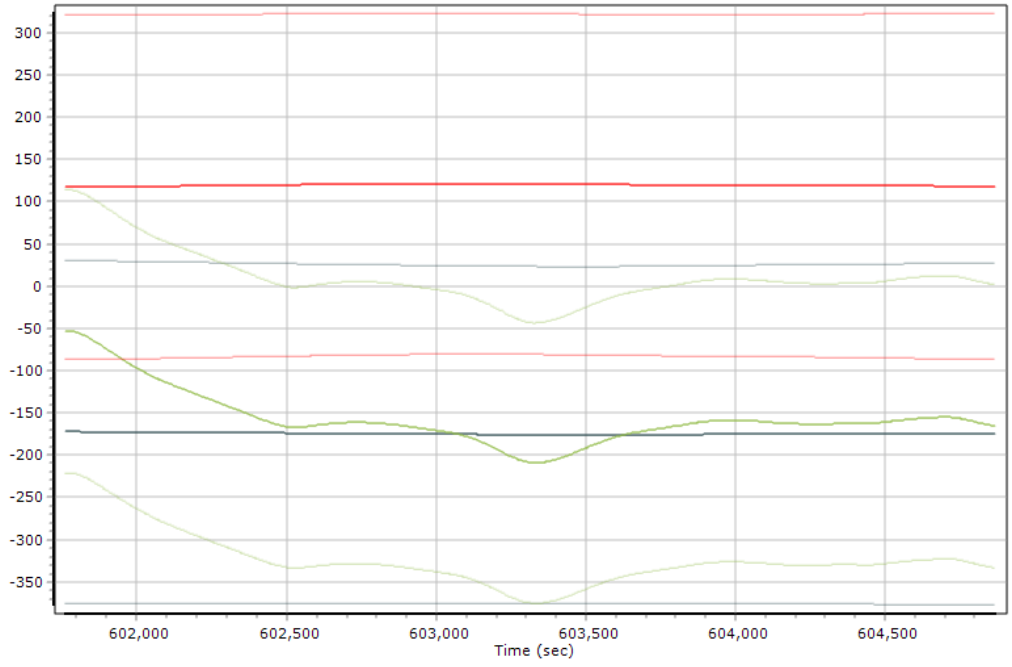
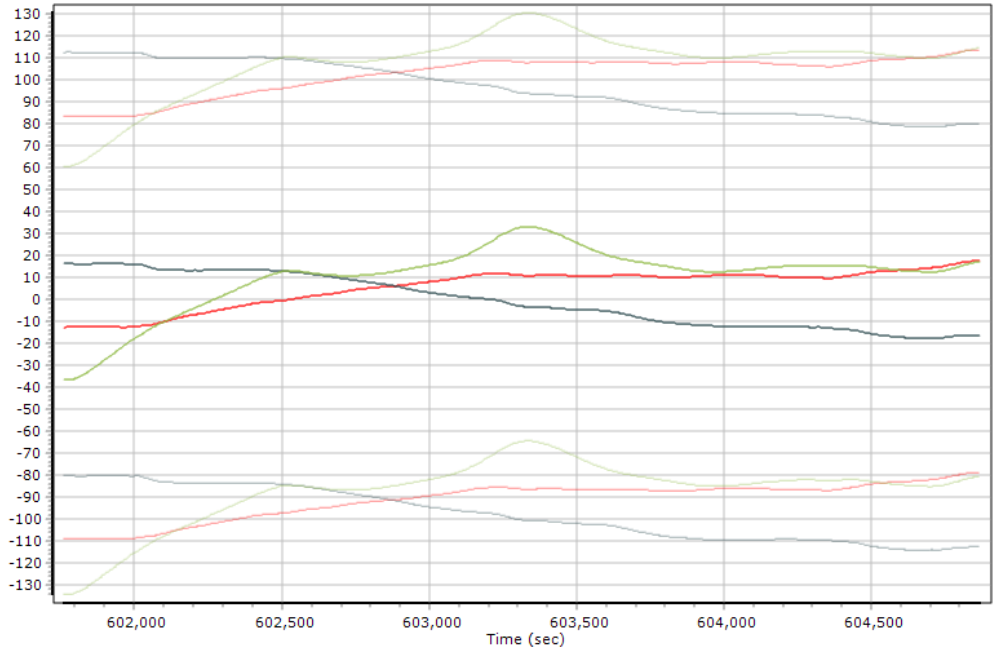
Processing Mode

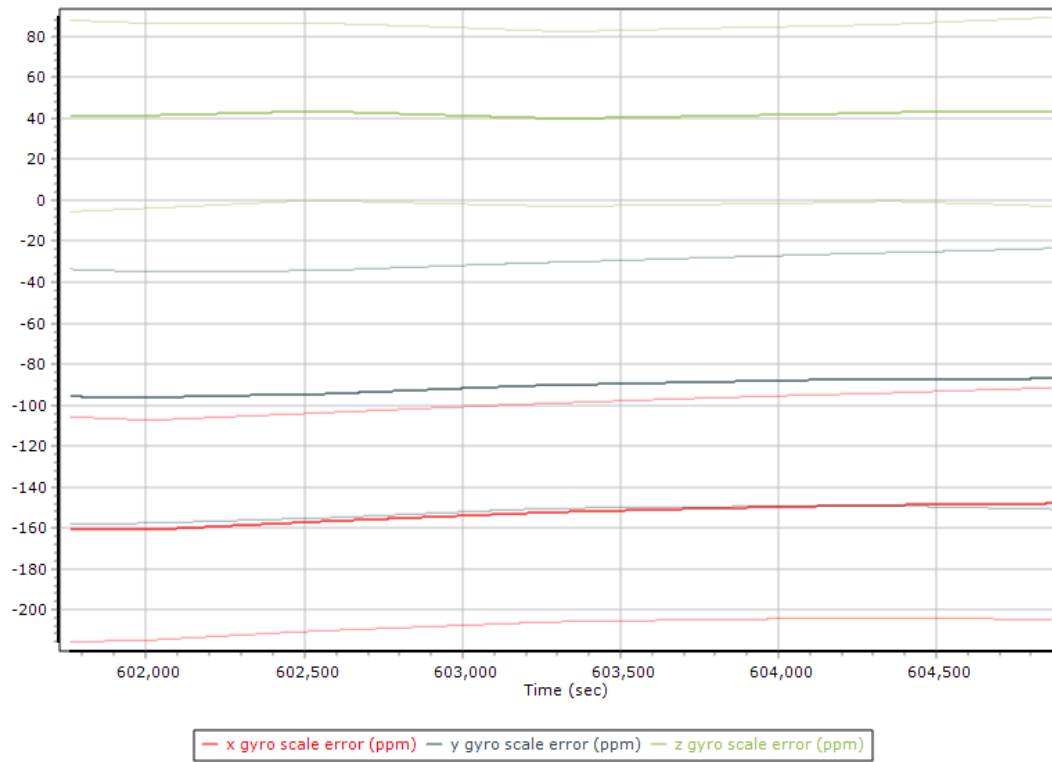
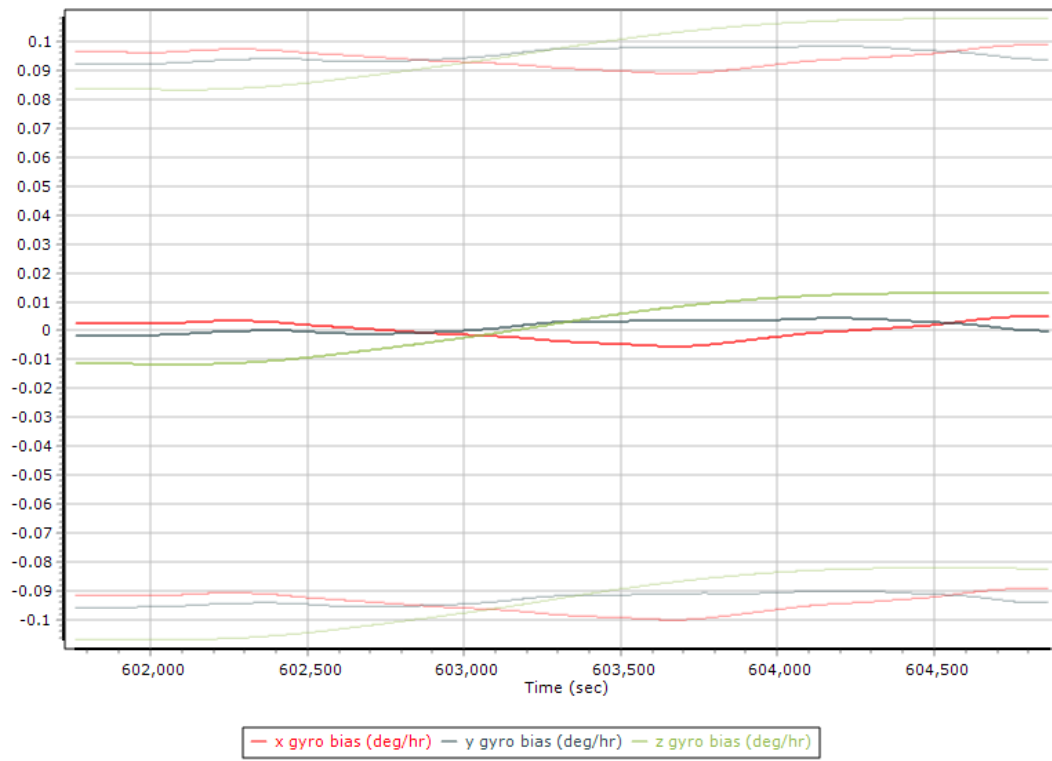


Forward Reverse

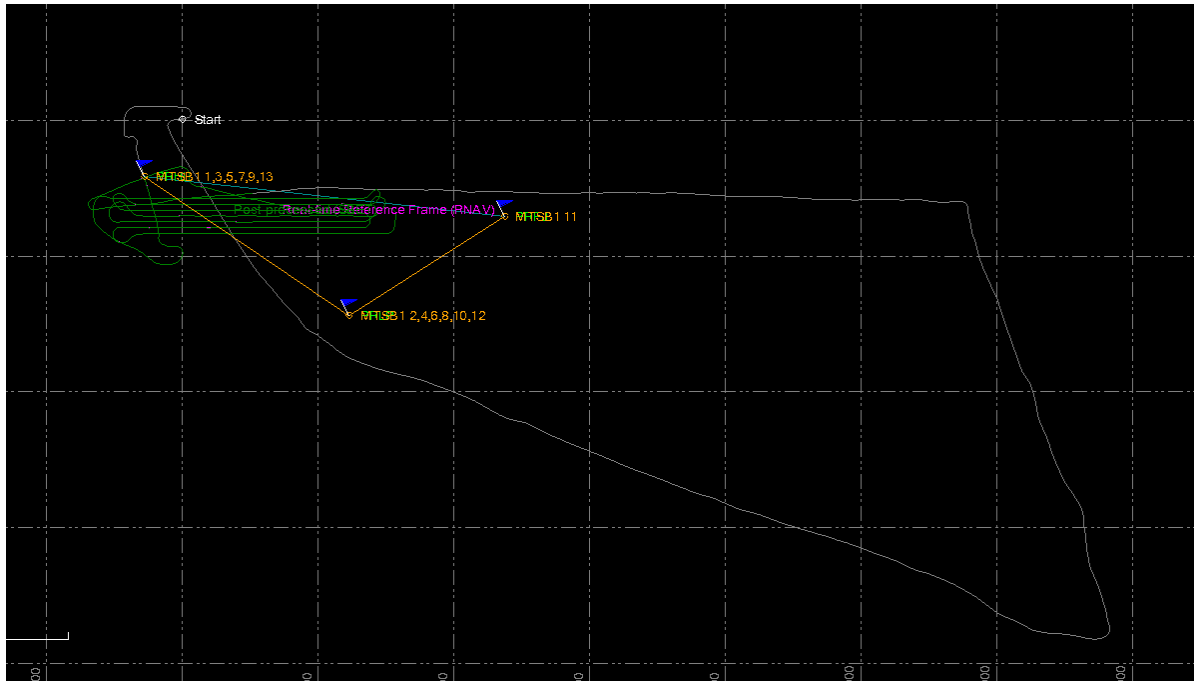
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





AZT18147A



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.

Timing

Start

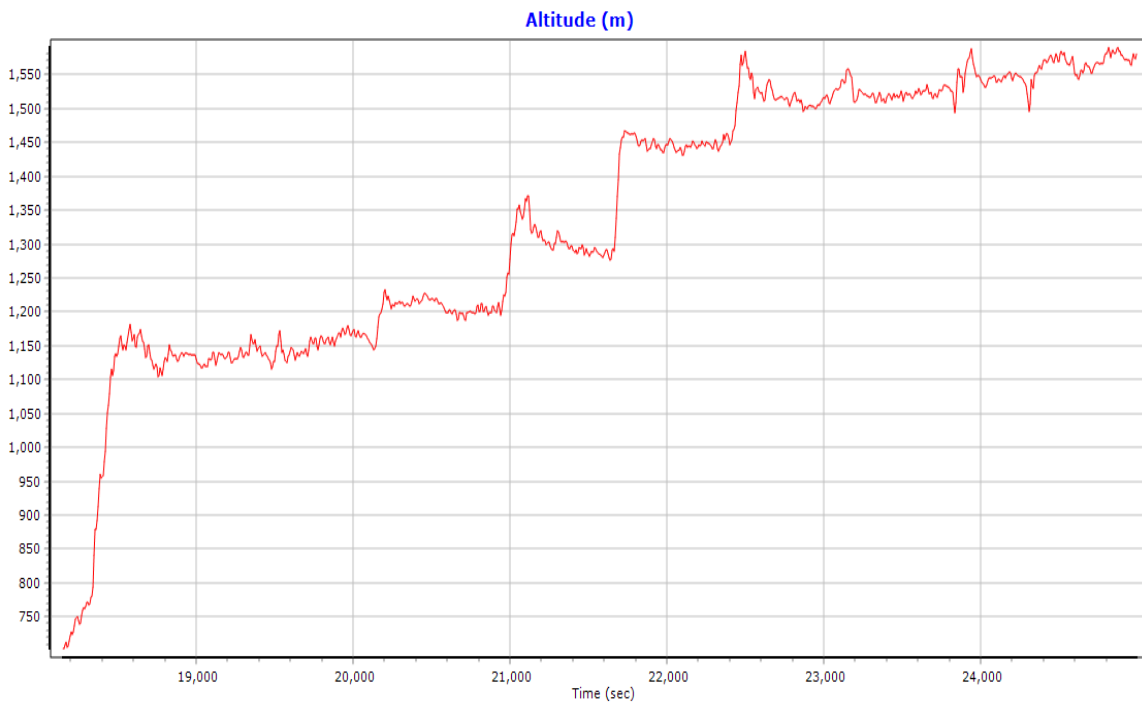
End

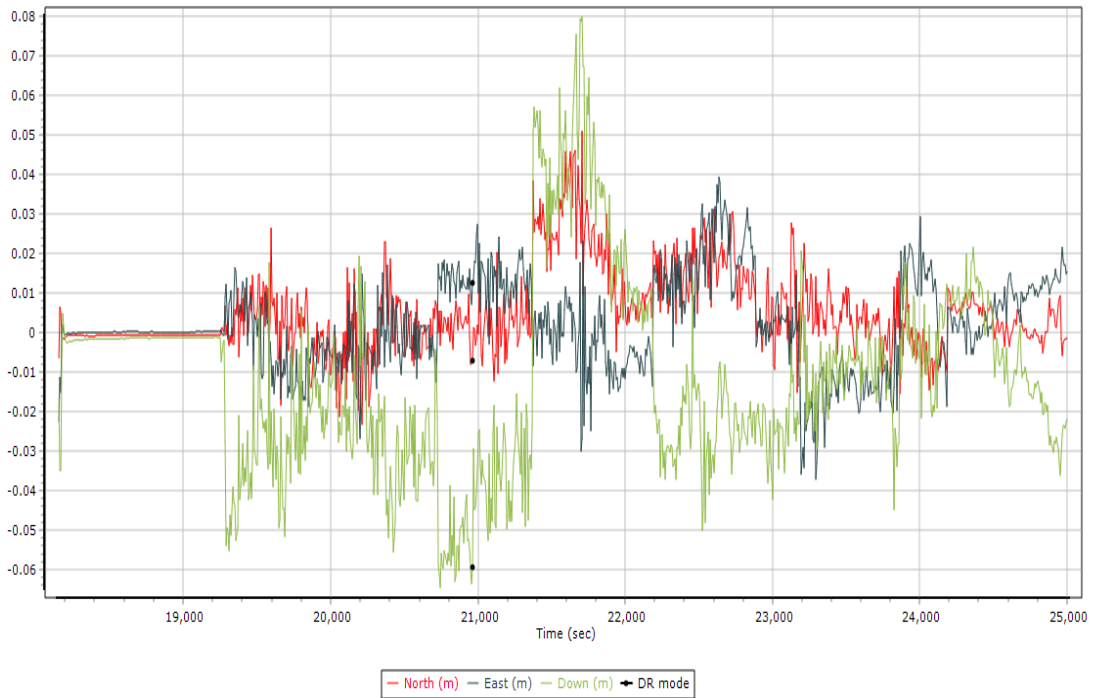
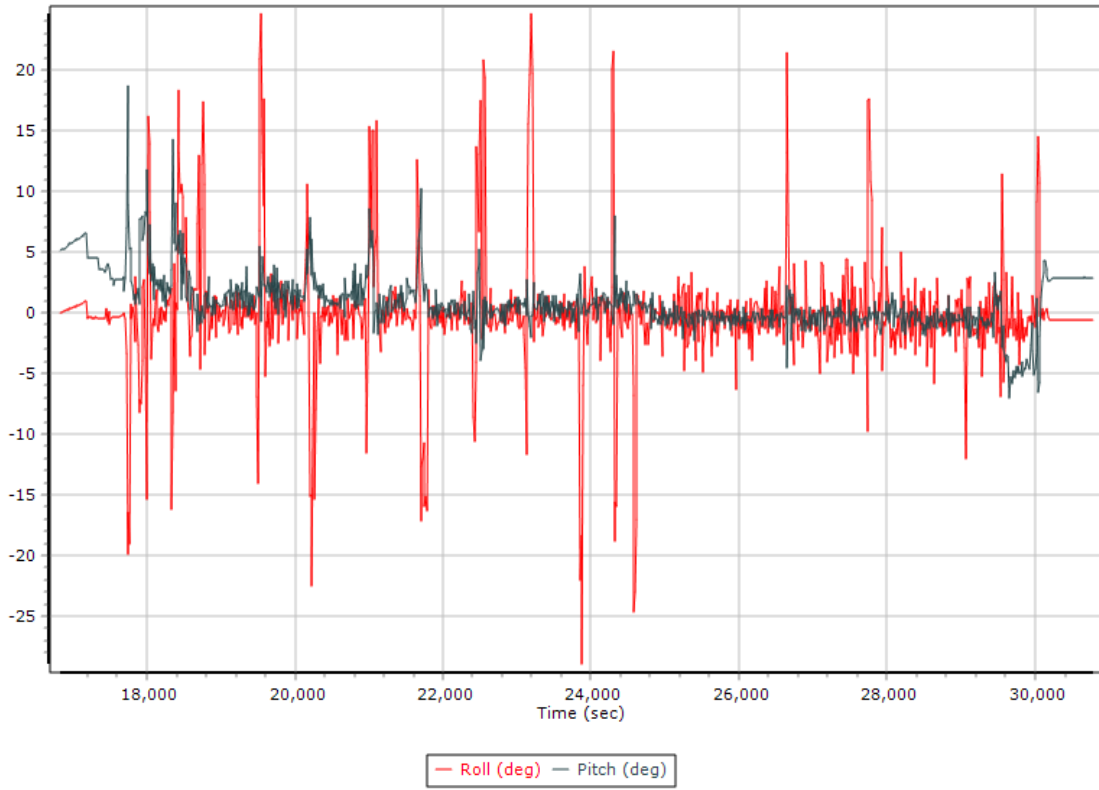
Entire time interval

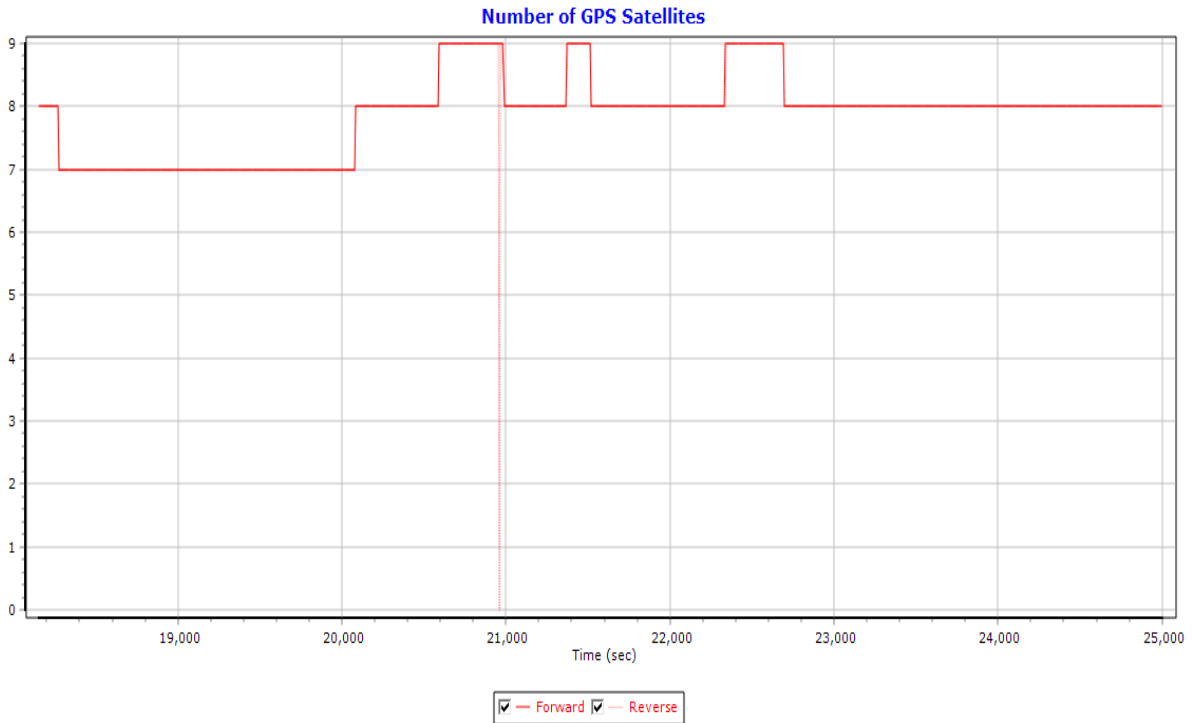
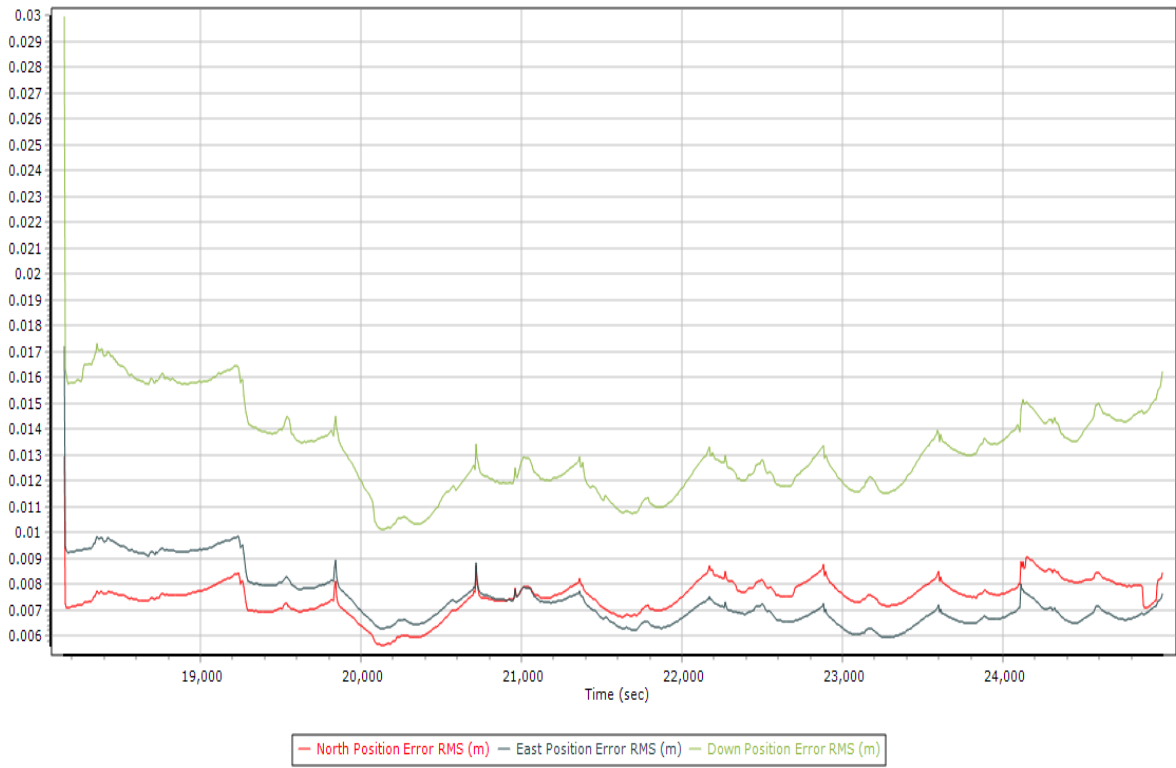
Seconds of start week

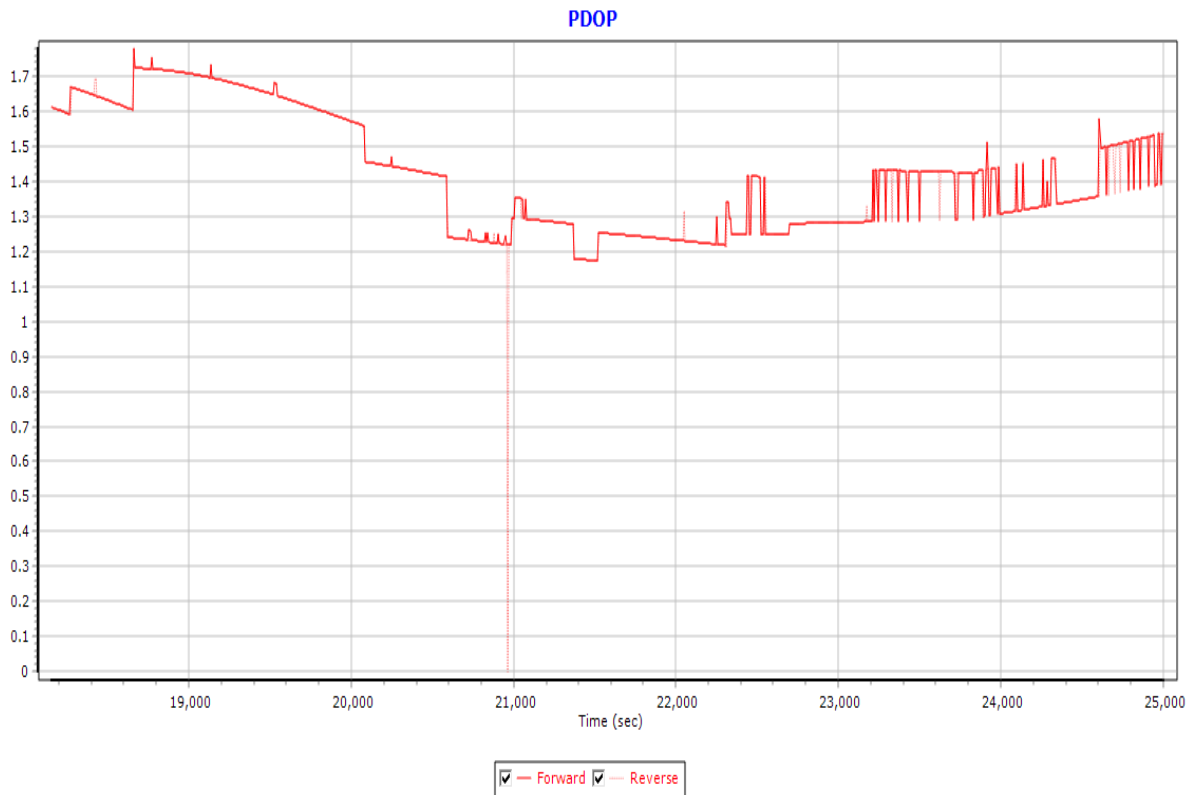
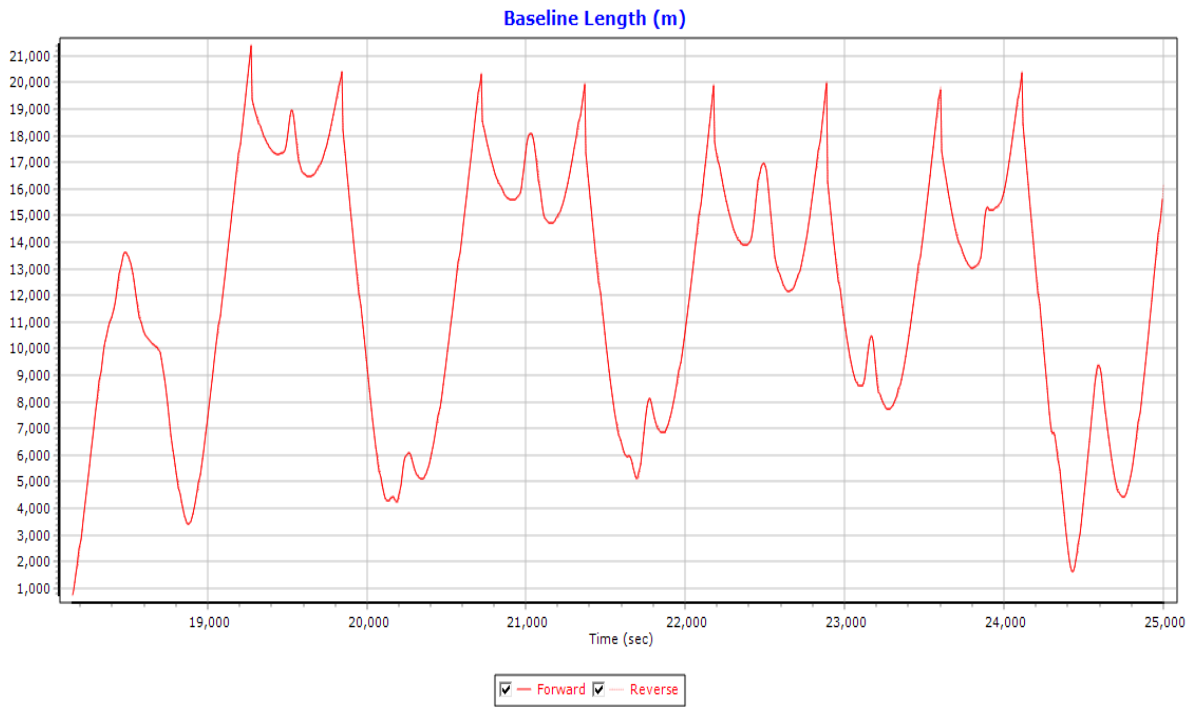
UTC Offset

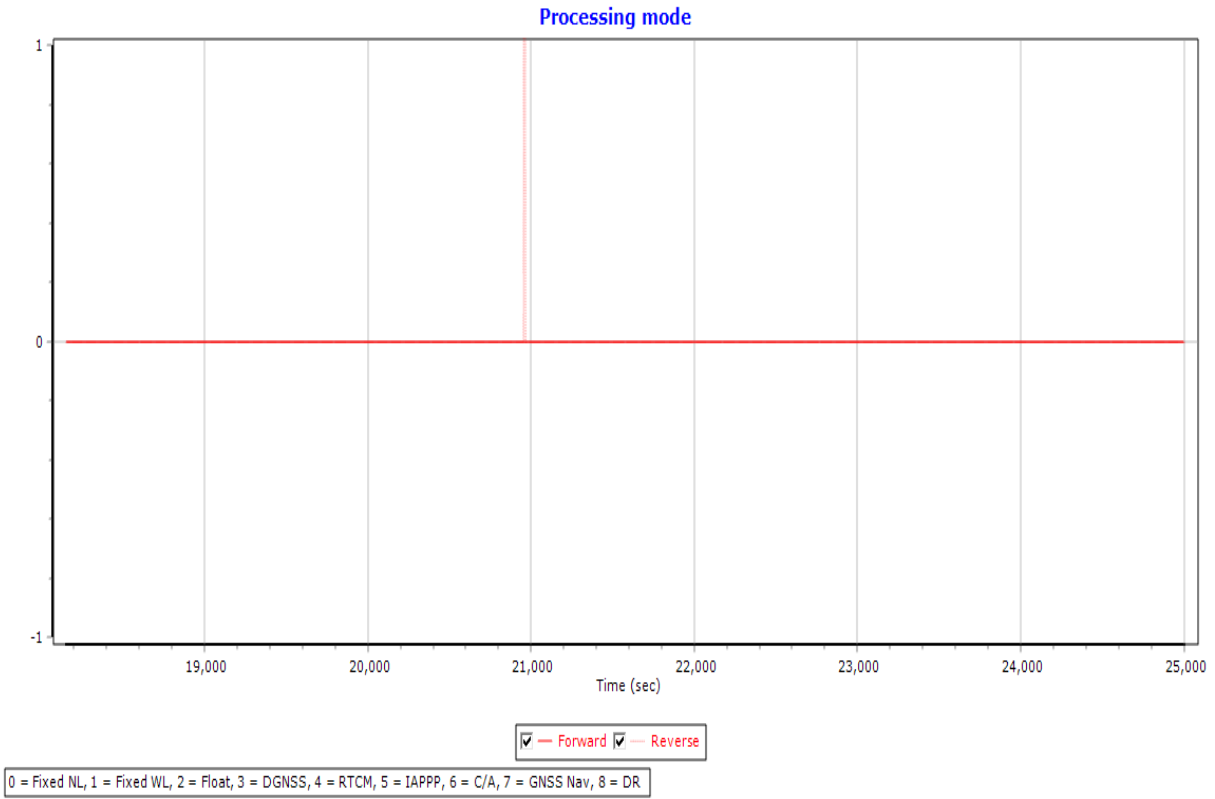
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



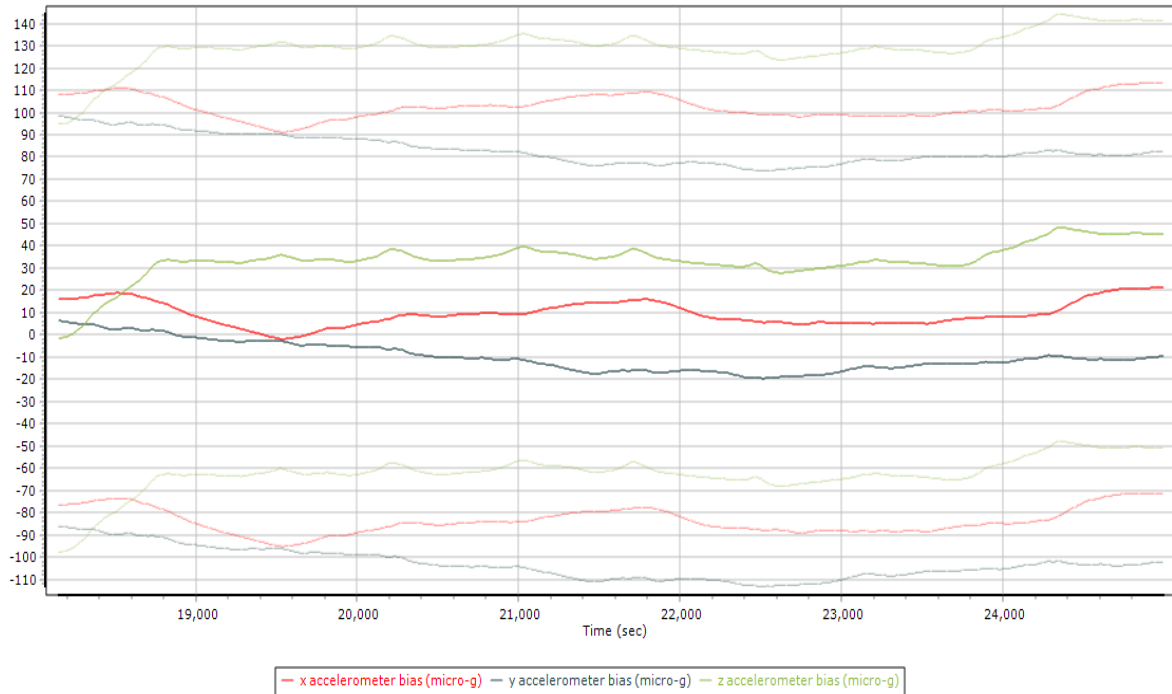


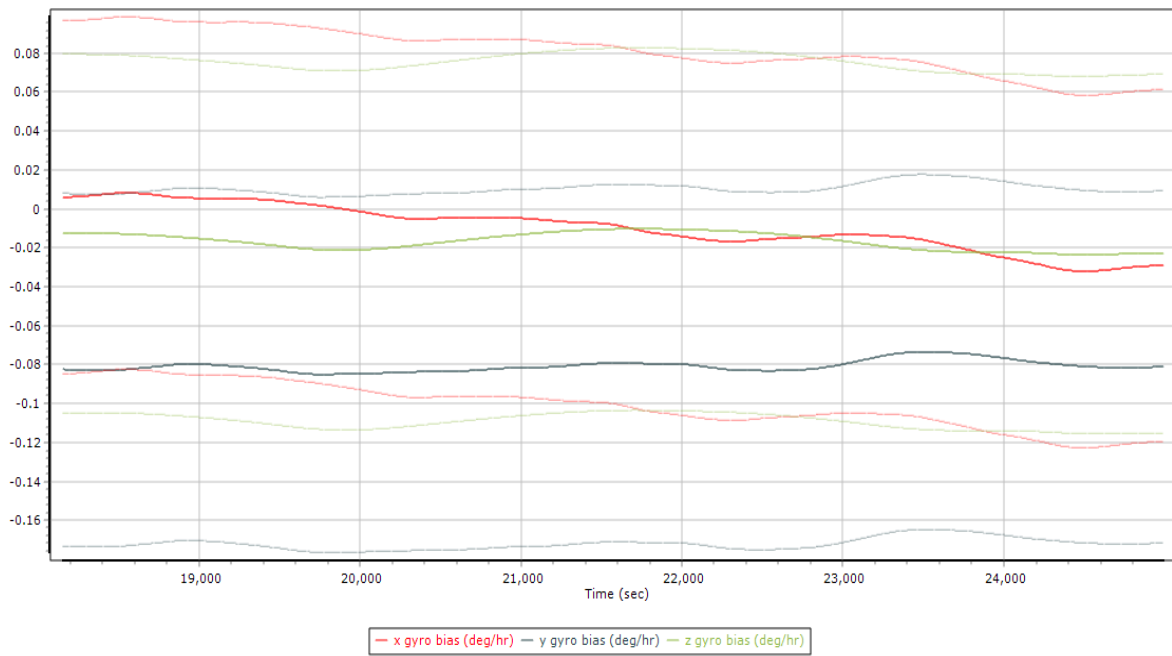
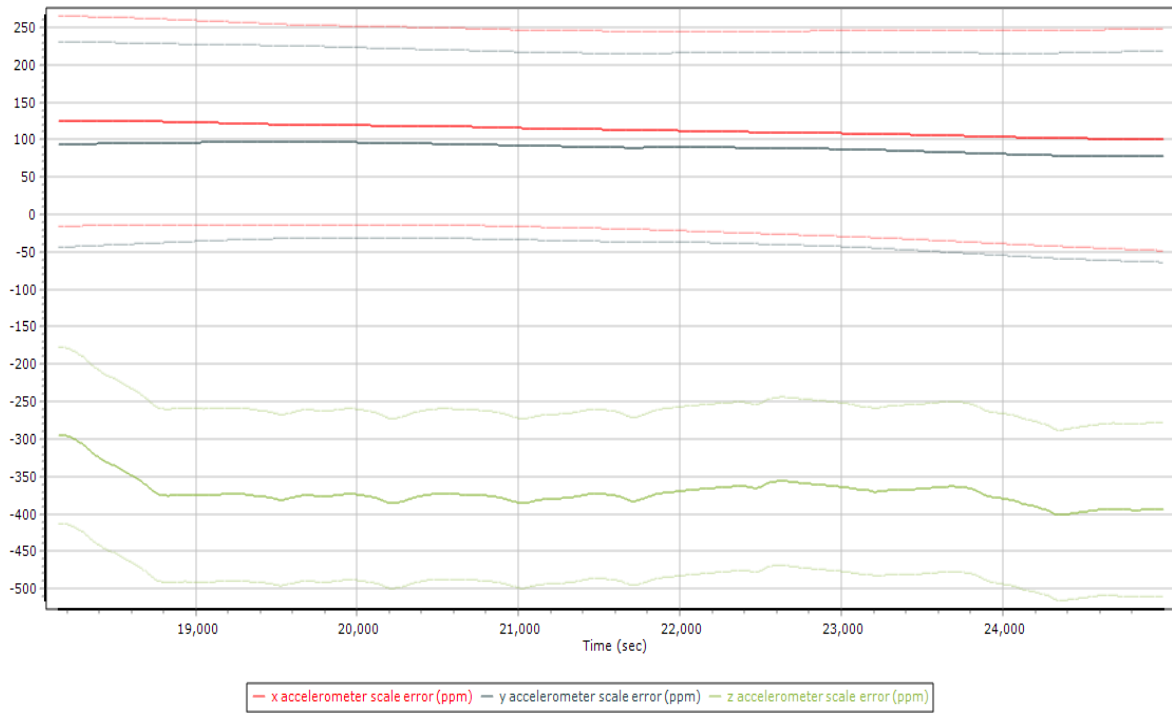


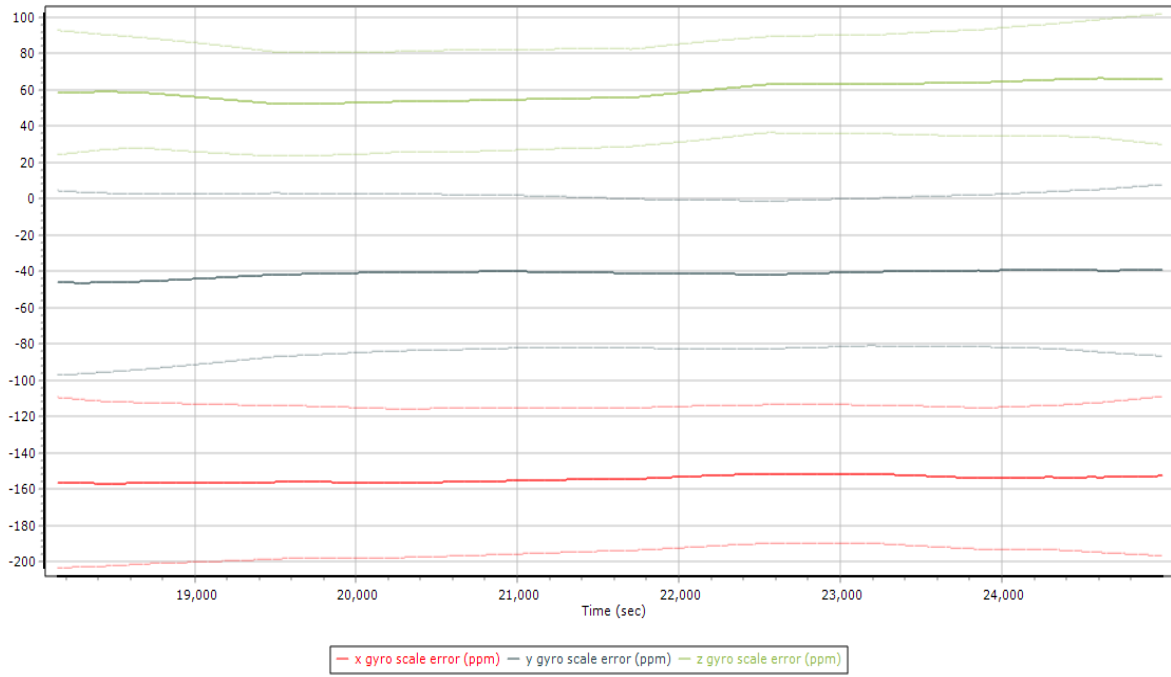




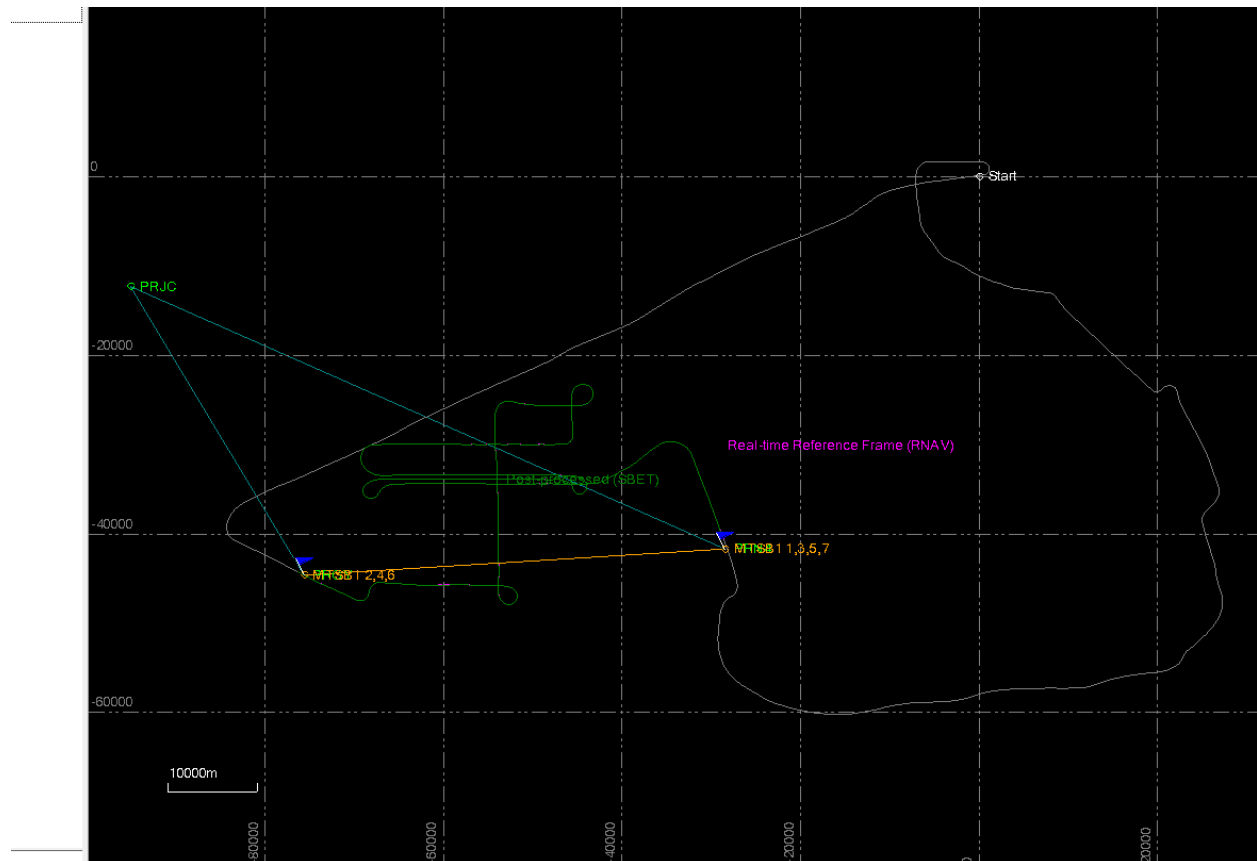
Sensor Errors







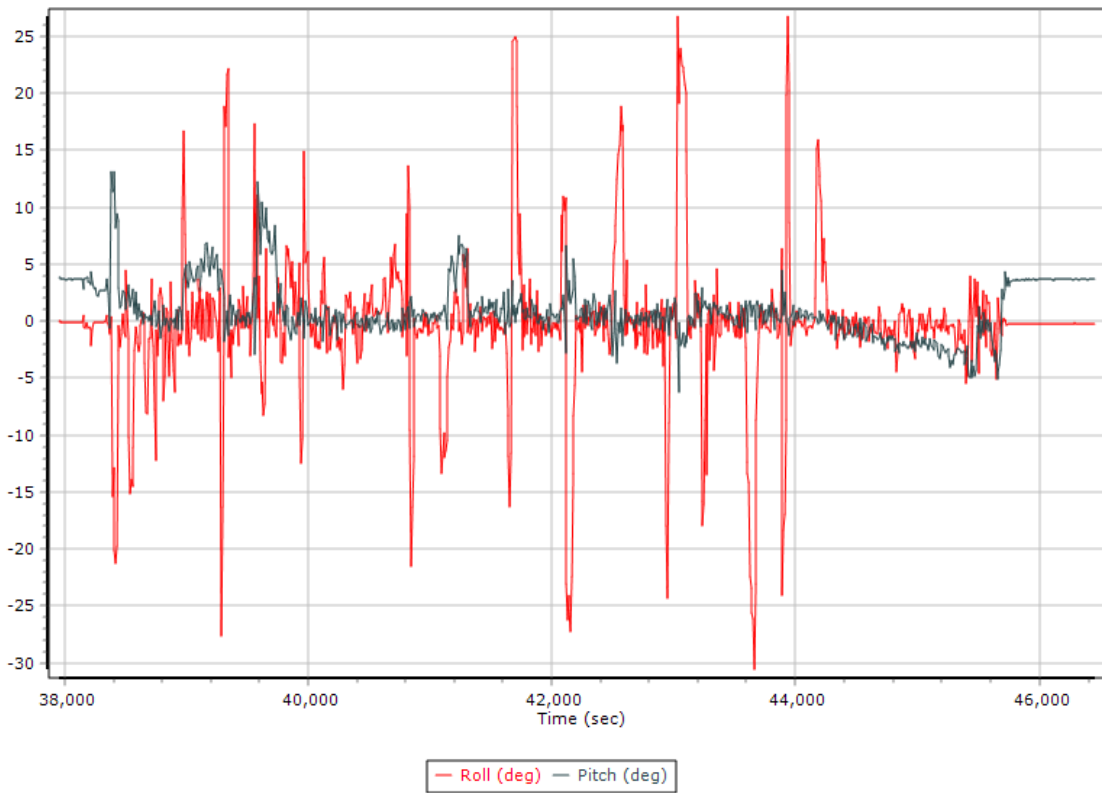
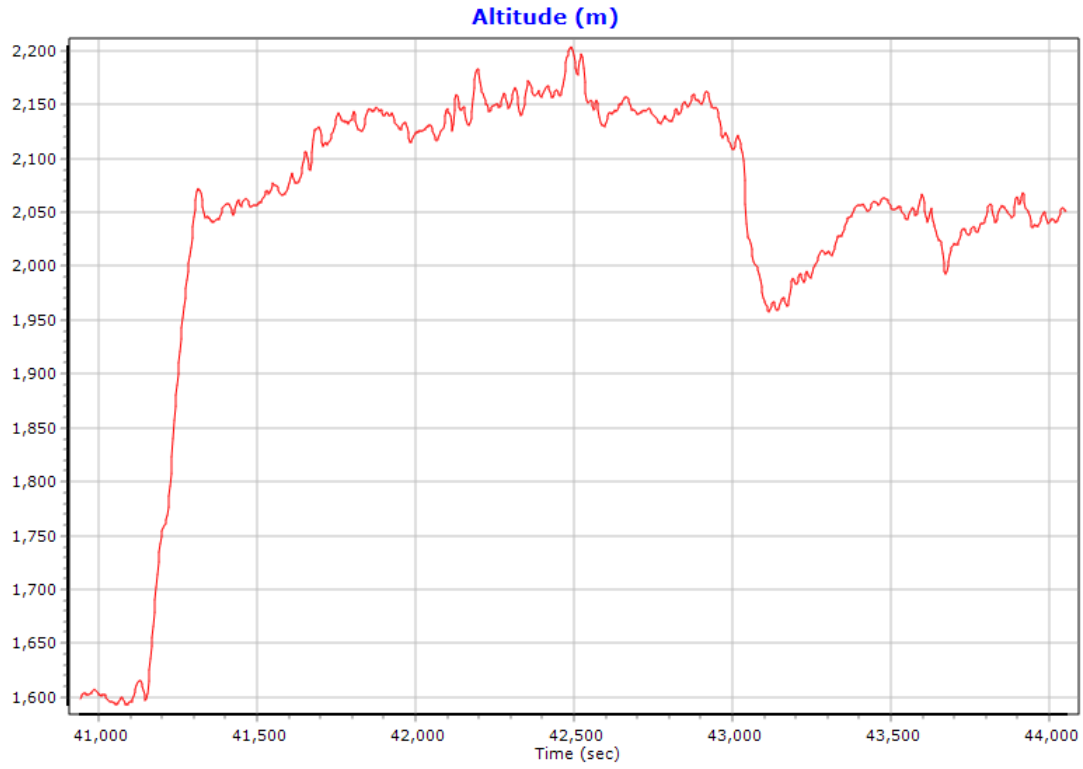
AZT18147B

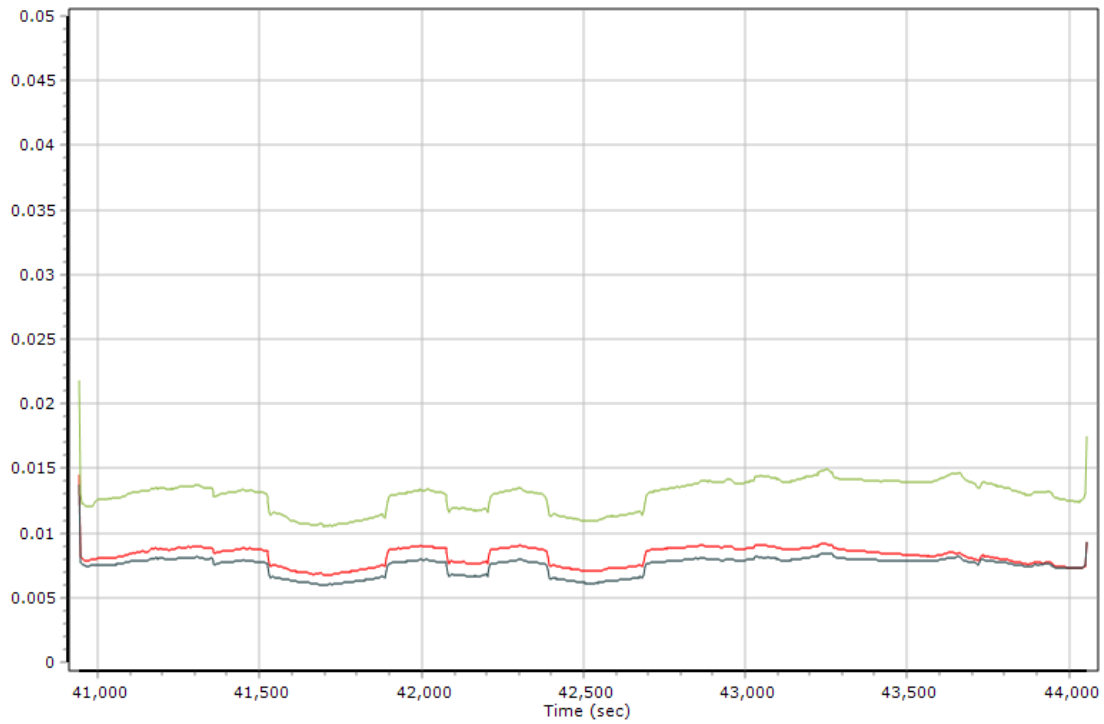


Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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		

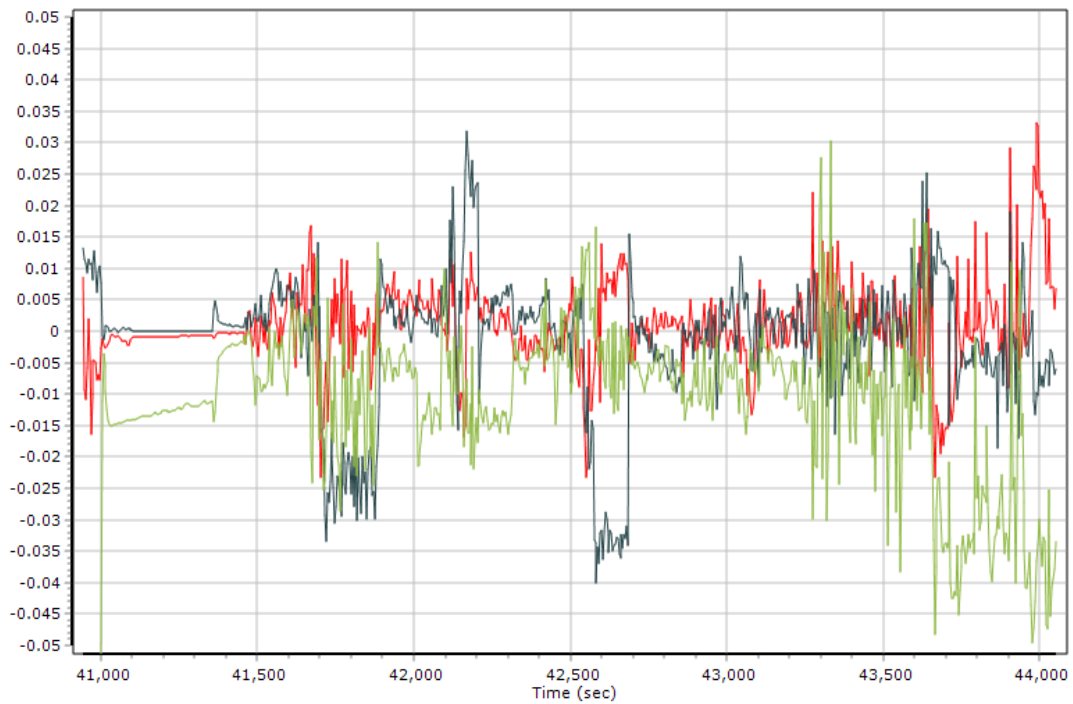
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

Timing										
Start	<input type="text" value="40939.602"/>									
End	<input type="text" value="44058.325"/>									
<input type="checkbox"/> Entire time interval										
<input checked="" type="checkbox"/> Seconds of start week										
UTC Offset	<input type="text" value="18.000"/>									
		<table border="1"><thead><tr><th>Data</th><th>Incr. (sec)</th></tr></thead><tbody><tr><td>Output Record</td><td>0.005000</td></tr><tr><td>IMU</td><td>0.005000</td></tr><tr><td>Primary GNSS</td><td>1.000000</td></tr></tbody></table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000
Data	Incr. (sec)									
Output Record	0.005000									
IMU	0.005000									
Primary GNSS	1.000000									

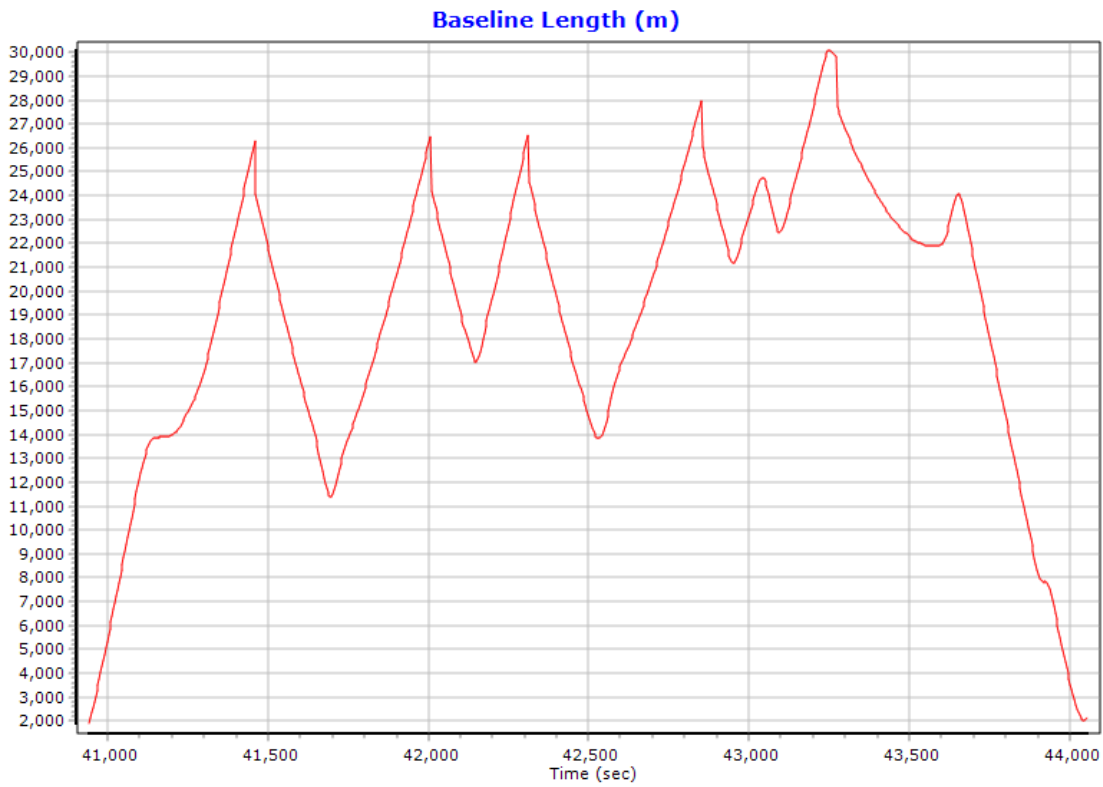
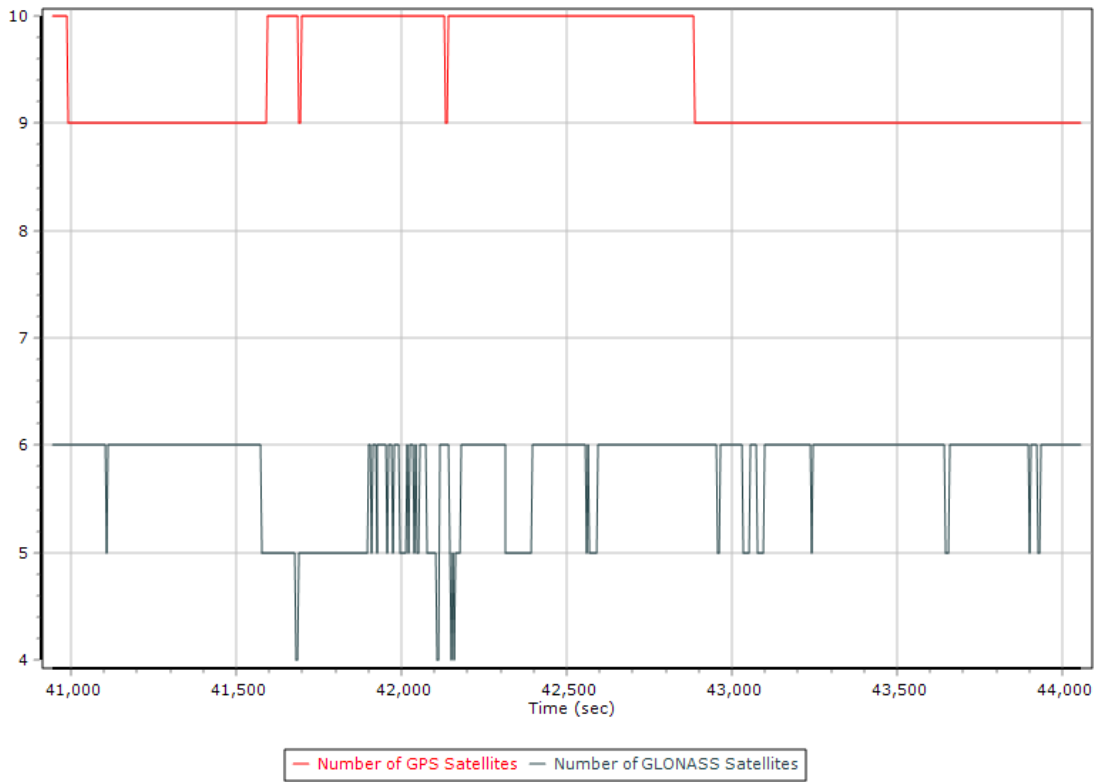




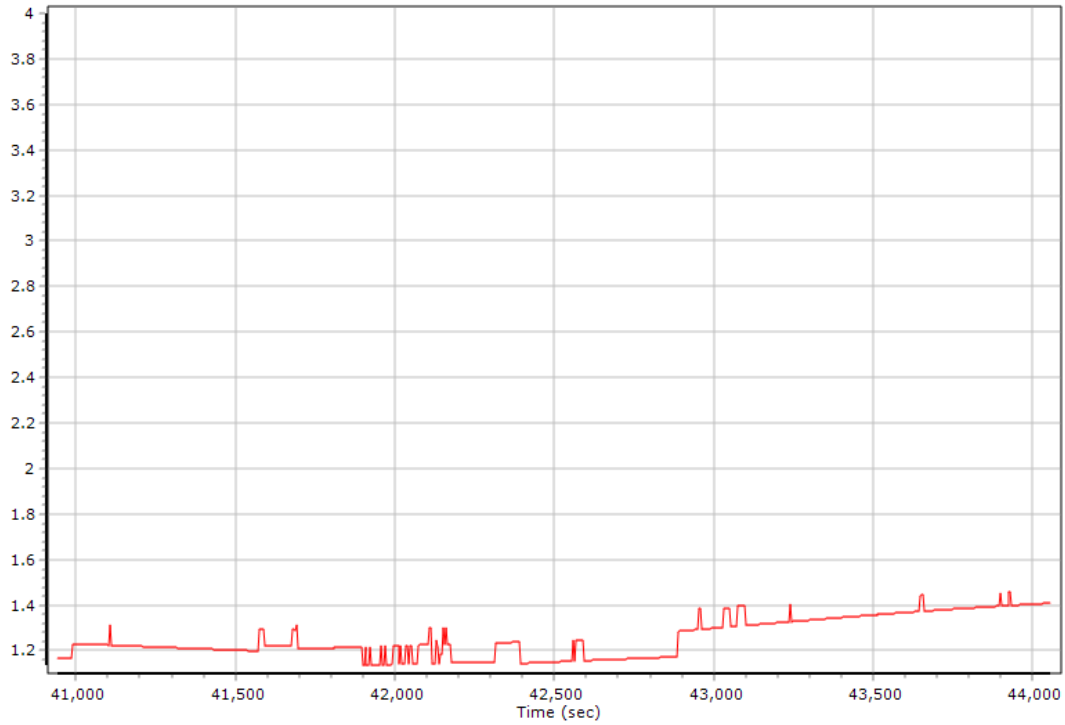
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



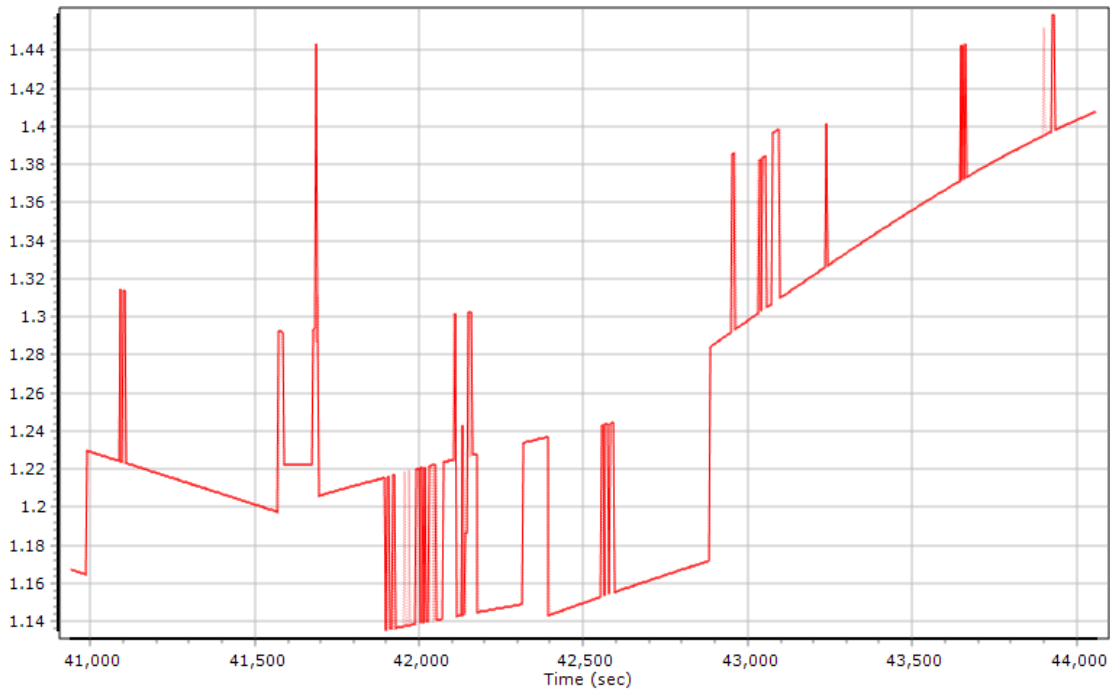
— North (m) — East (m) — Down (m) — DR mode



PDOP

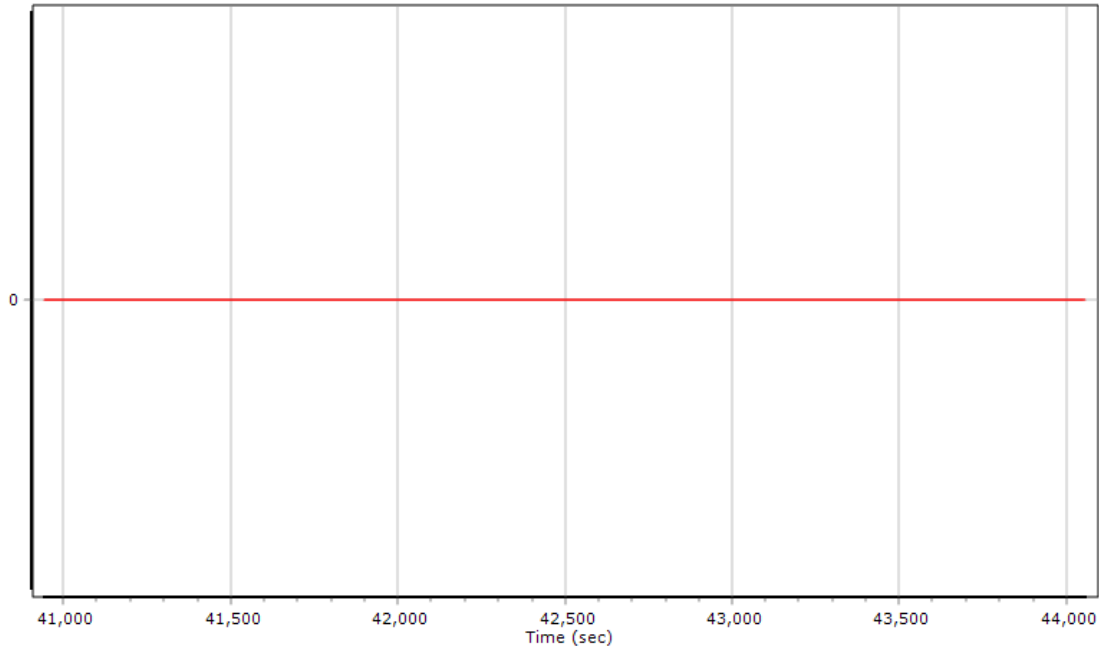


PDOP



Forward Reverse

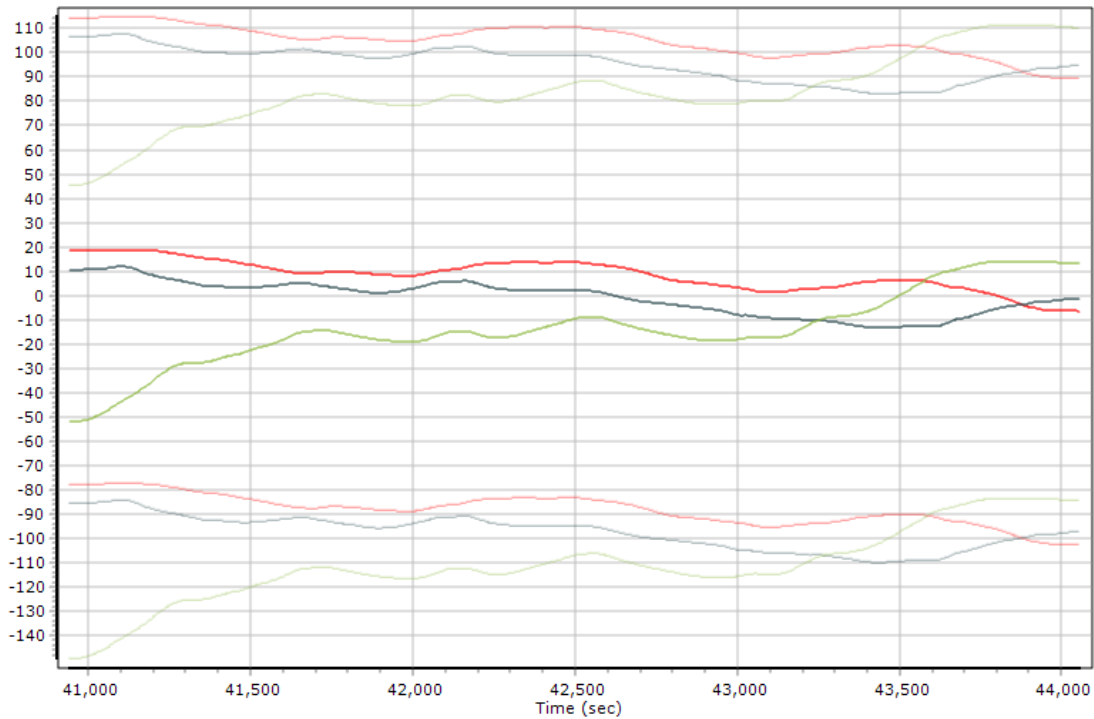
Processing Mode



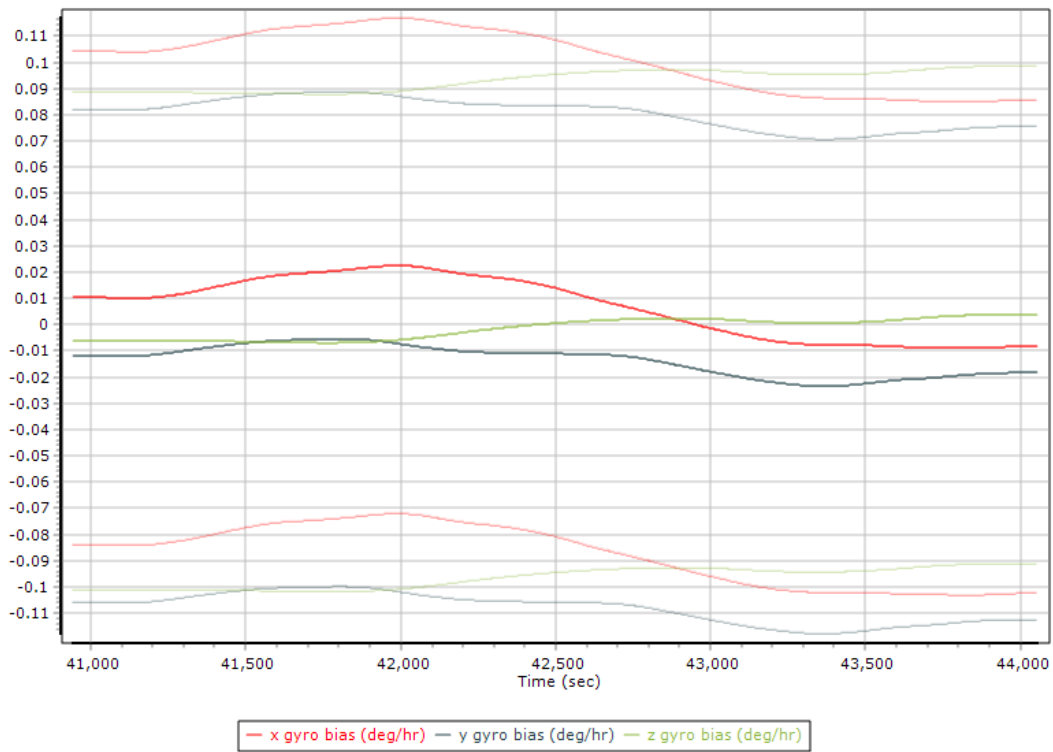
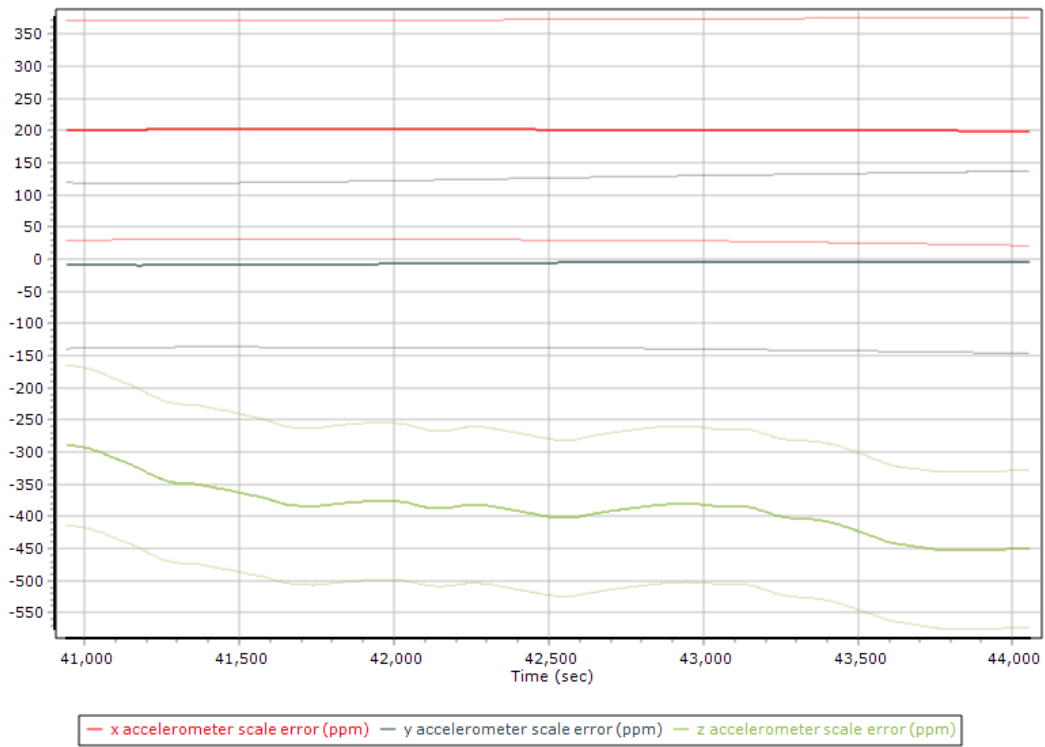
Forward Reverse

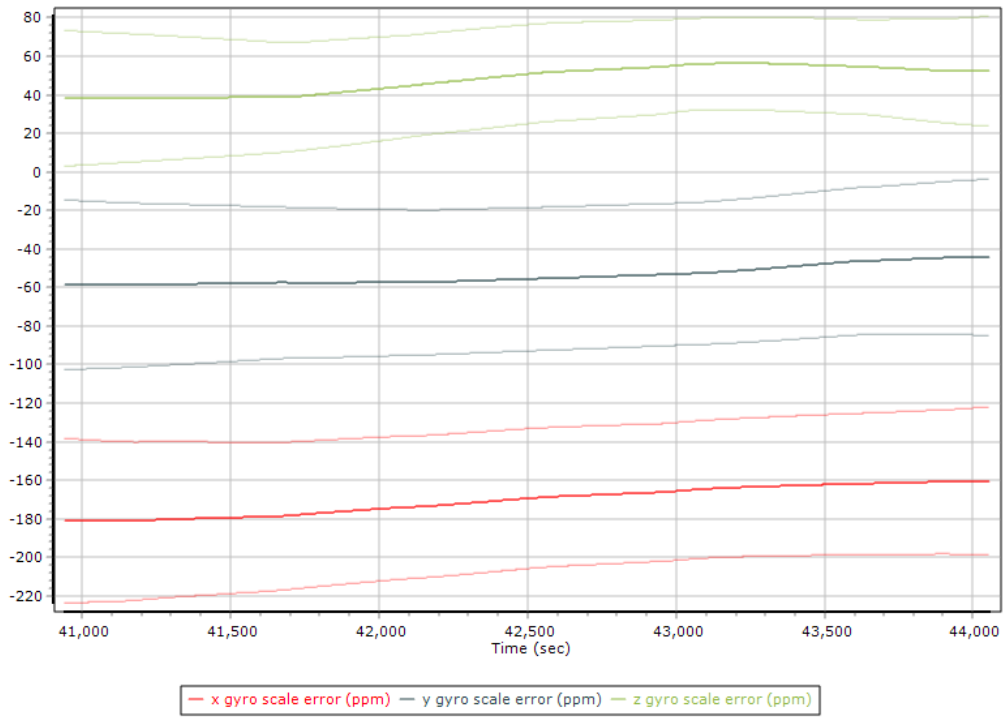
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

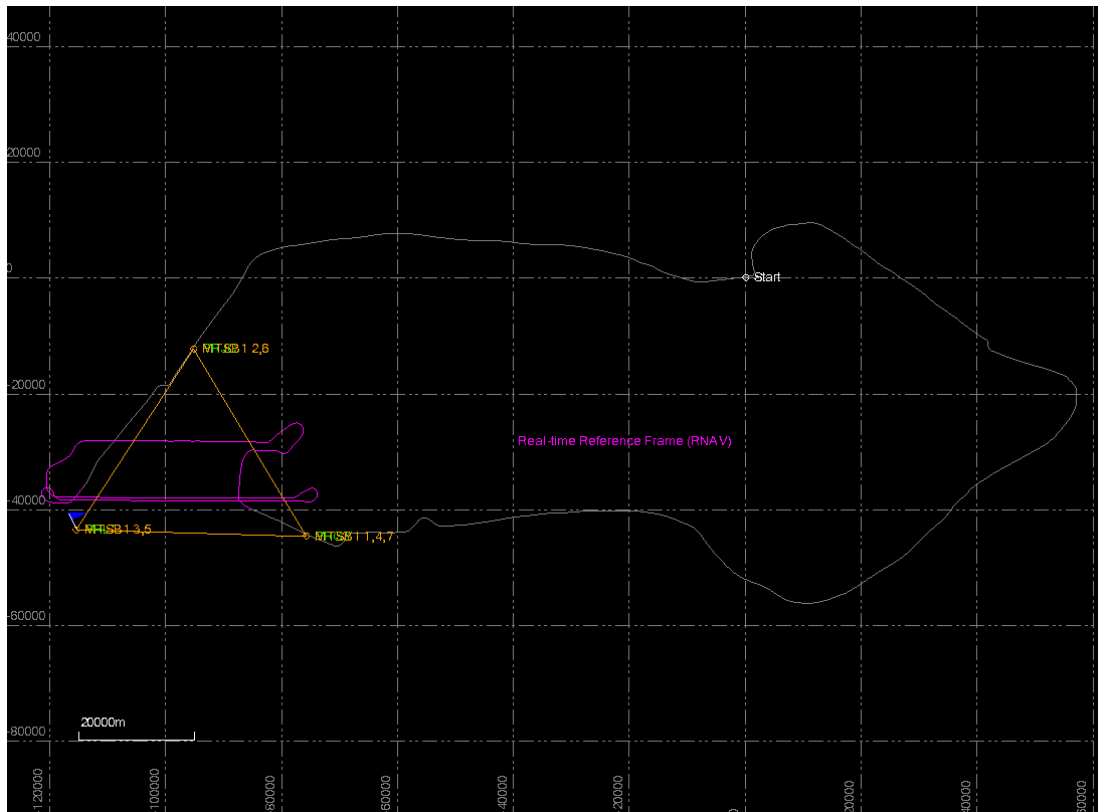


— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)





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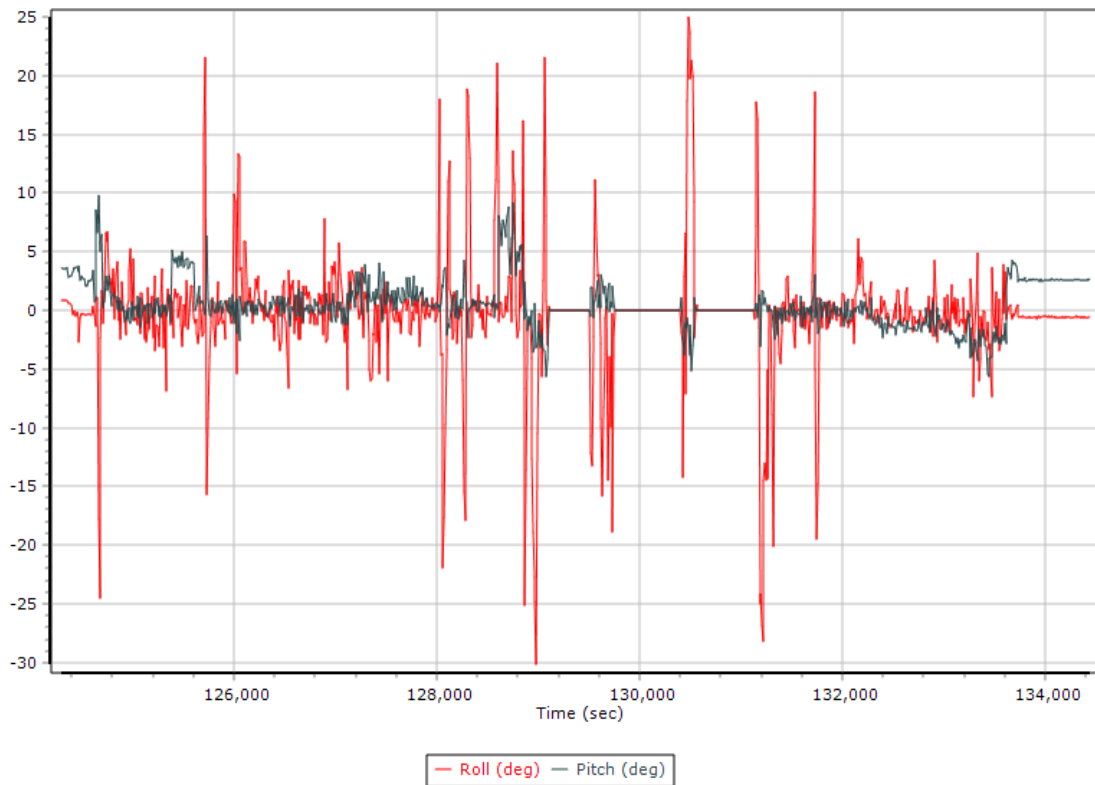
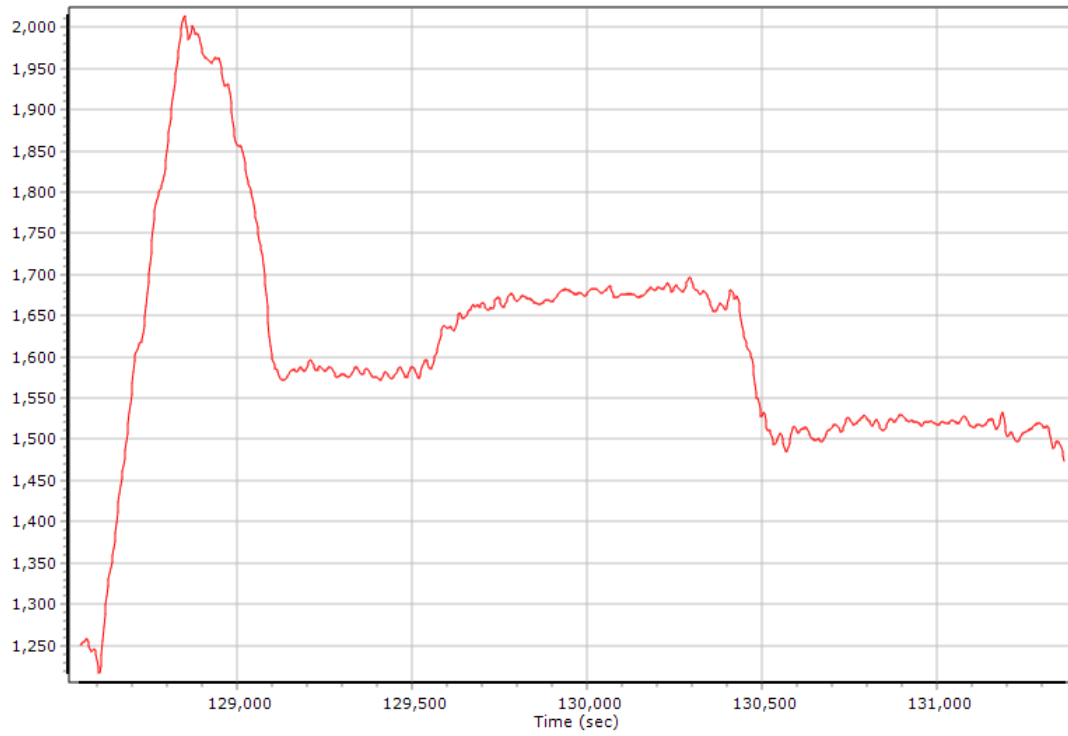


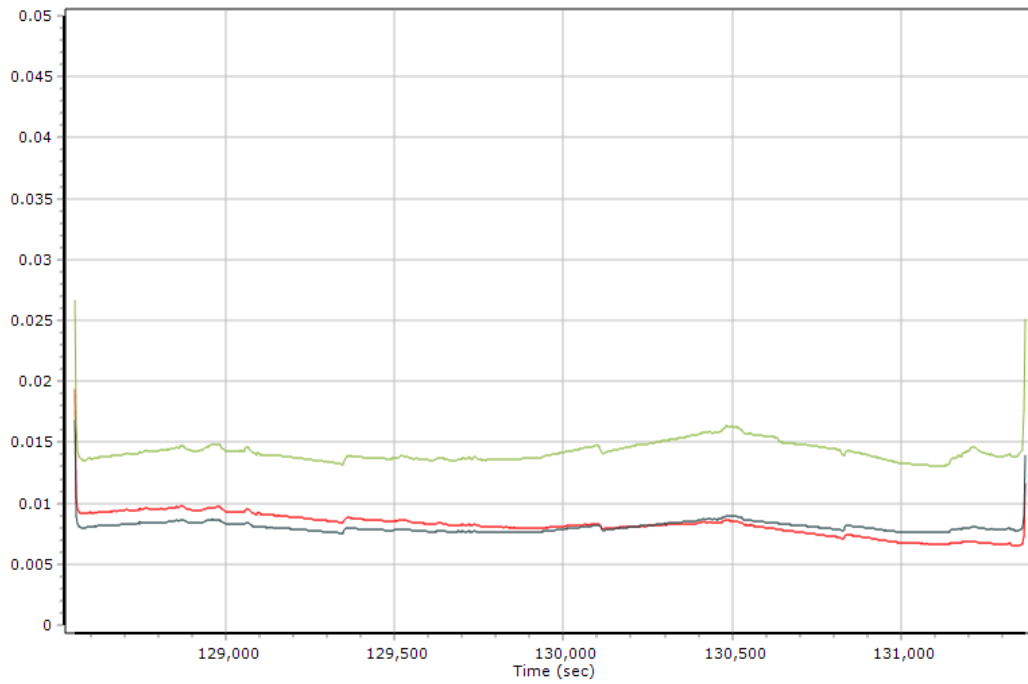
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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.

Timing									
Start	<input type="text" value="128551.385"/>								
End	<input type="text" value="131369.041"/>								
<input type="checkbox"/> Entire time interval									
<input checked="" type="checkbox"/> Seconds of start week									
UTC Offset	<input type="text" value="18.000"/>								
<table border="1"><thead><tr><th>Data</th><th>Incr. (sec)</th></tr></thead><tbody><tr><td>Output Record</td><td>0.005000</td></tr><tr><td>IMU</td><td>0.005000</td></tr><tr><td>Primary GNSS</td><td>1.000000</td></tr></tbody></table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000	<input type="text" value=""/>
Data	Incr. (sec)								
Output Record	0.005000								
IMU	0.005000								
Primary GNSS	1.000000								

Altitude (m)

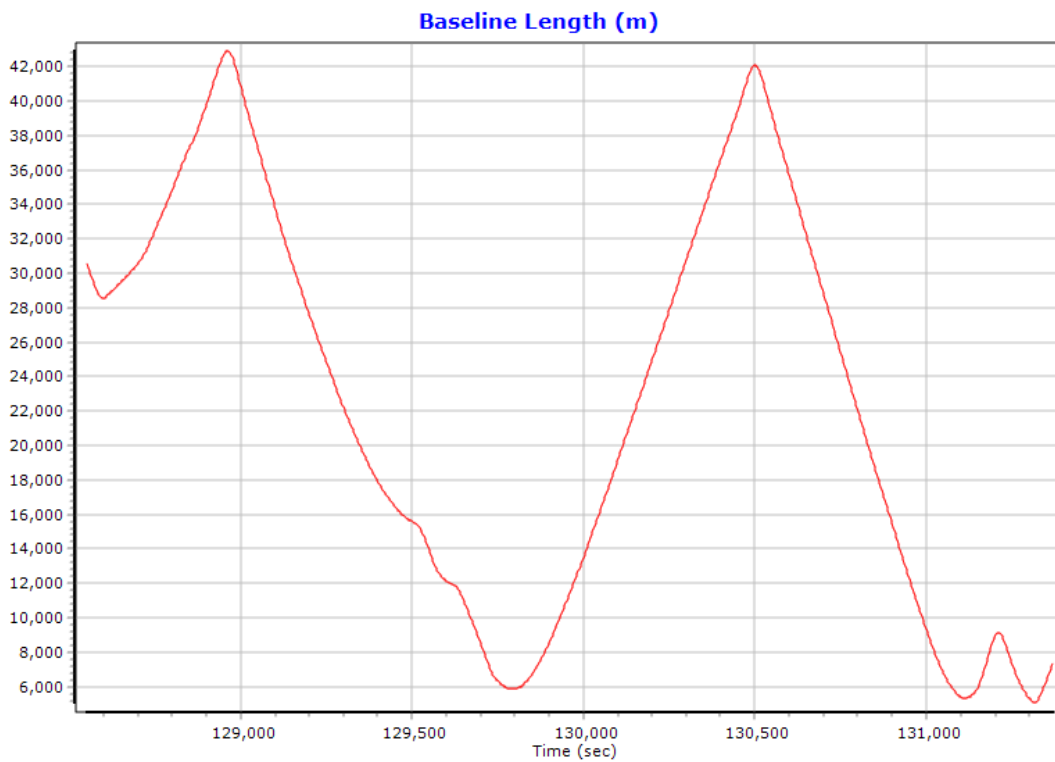
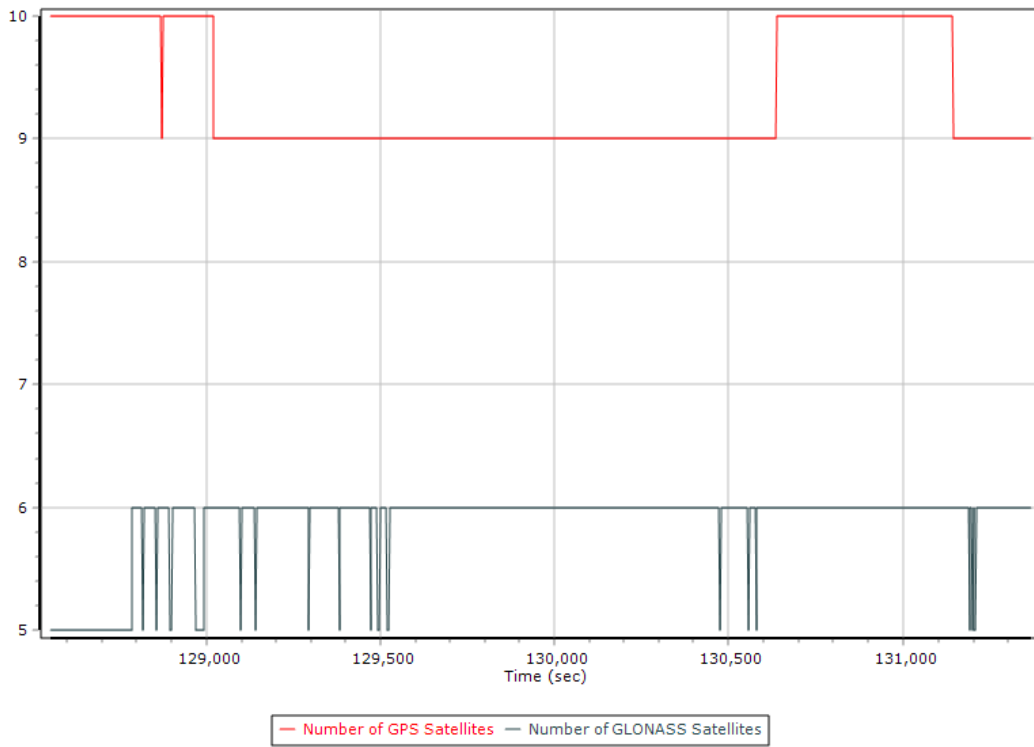




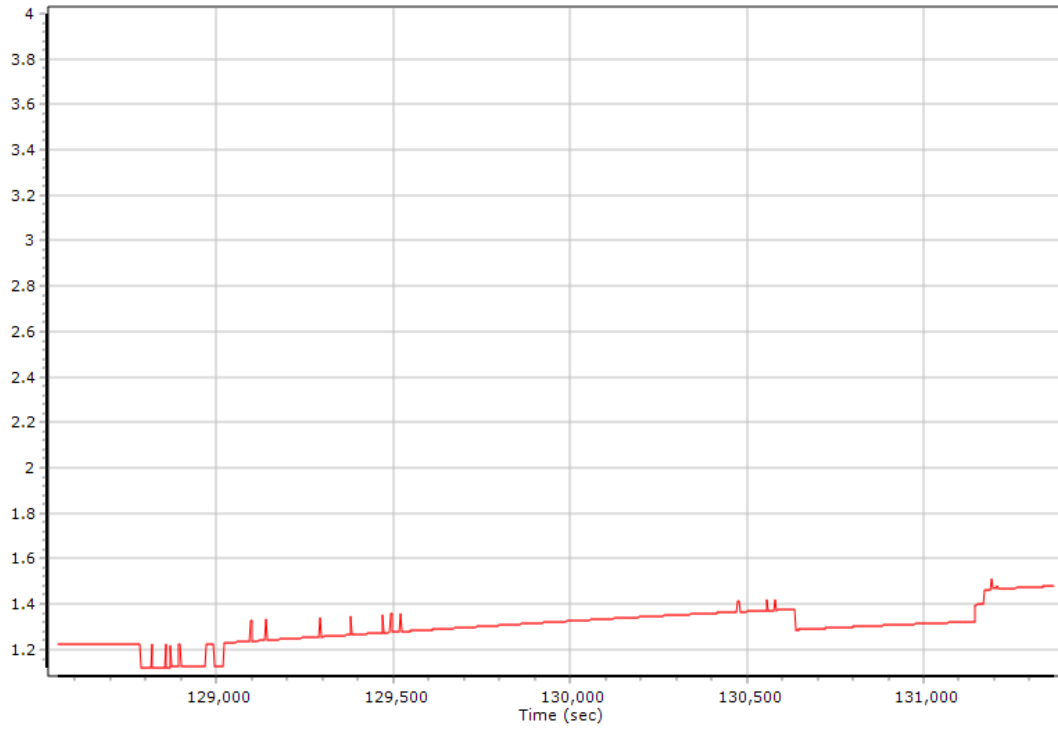
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



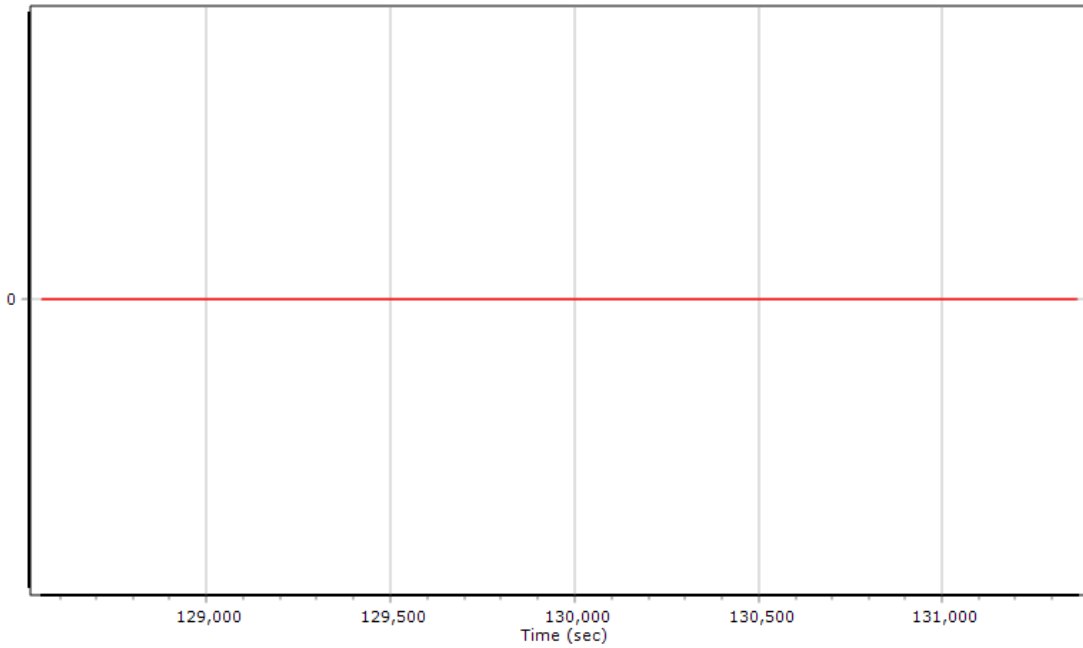
— North (m) — East (m) — Down (m) → DR mode



PDOP



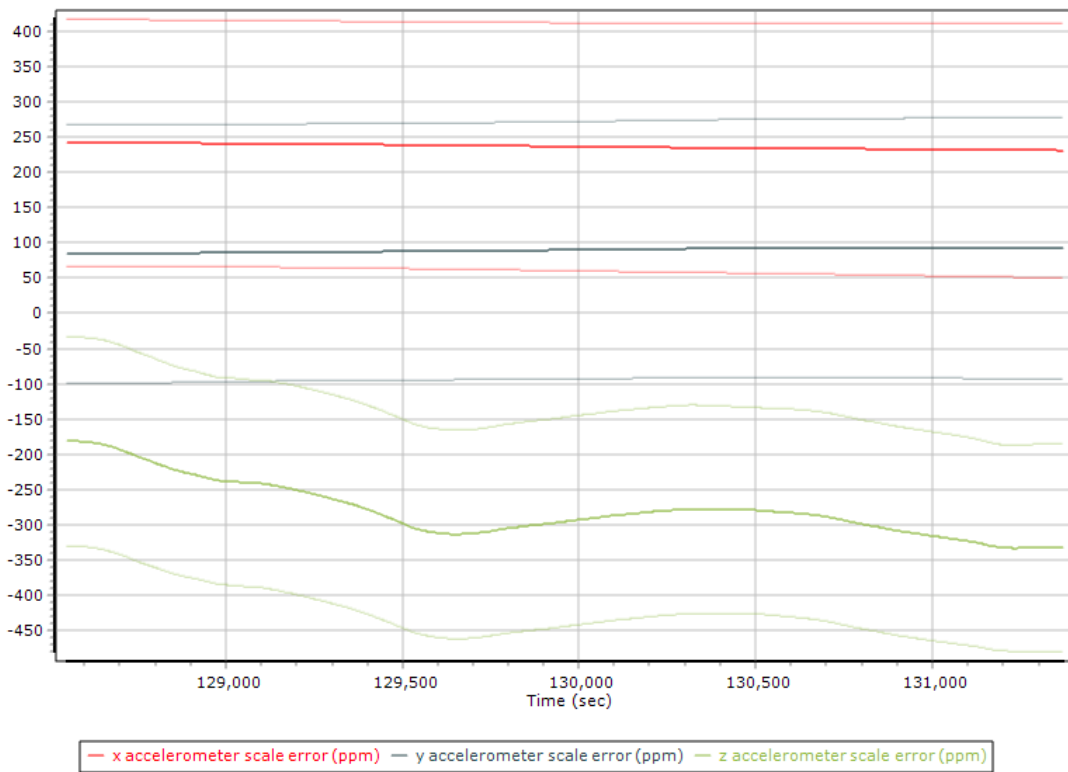
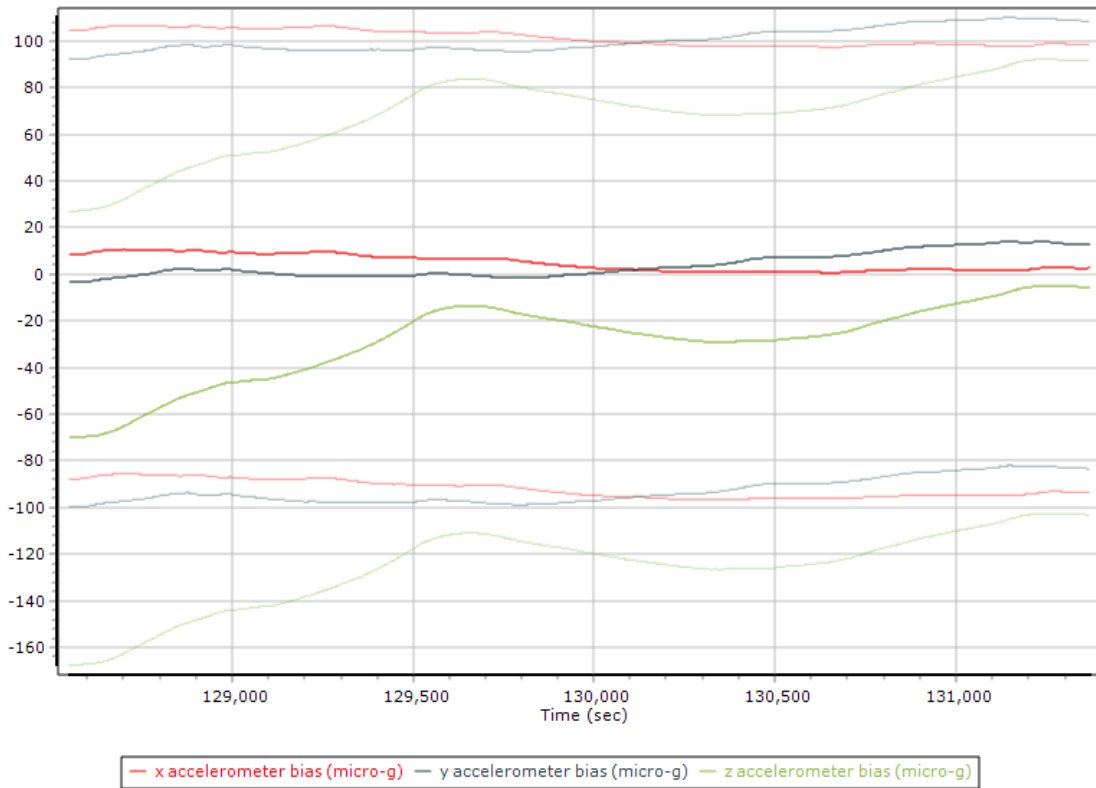
Processing Mode

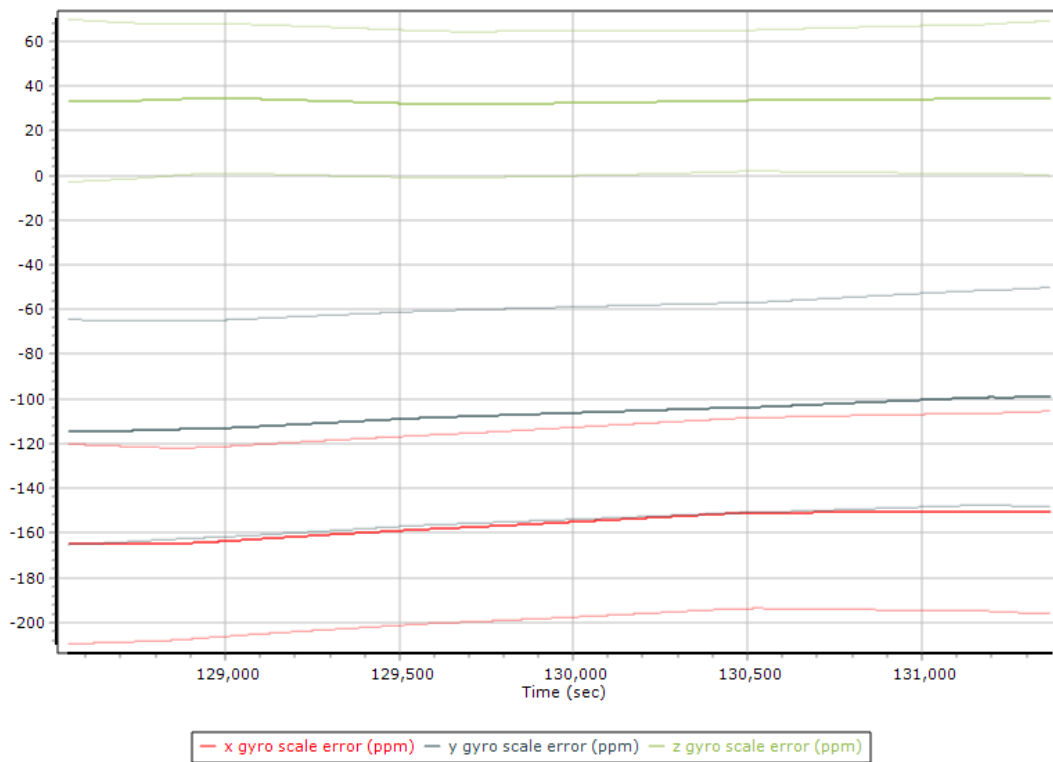
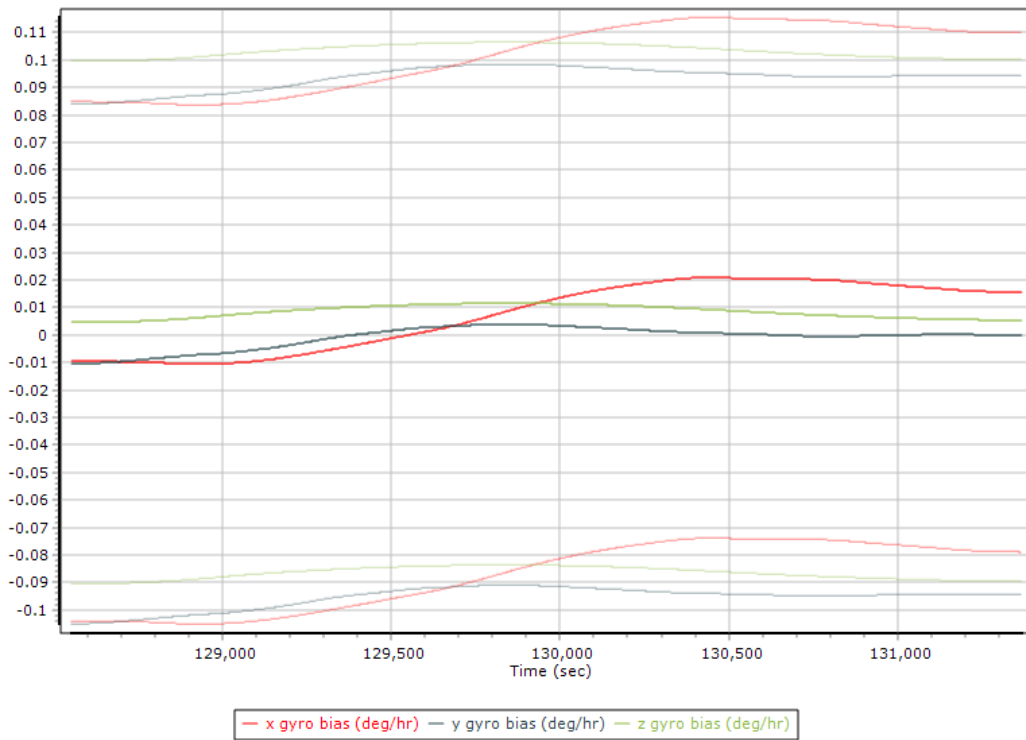


Forward Reverse

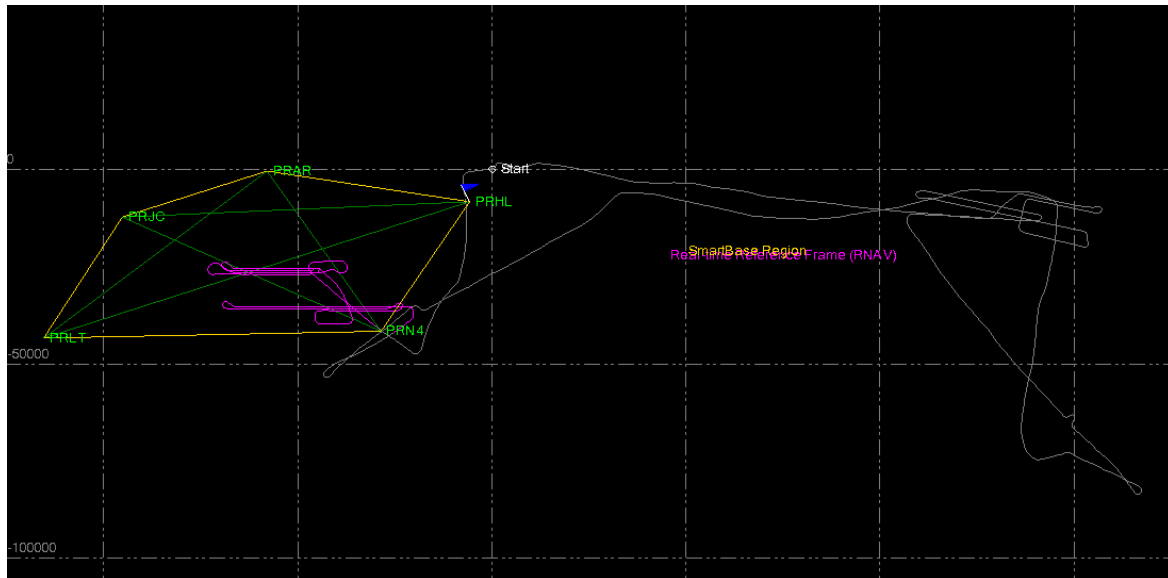
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Error





AZT18148B

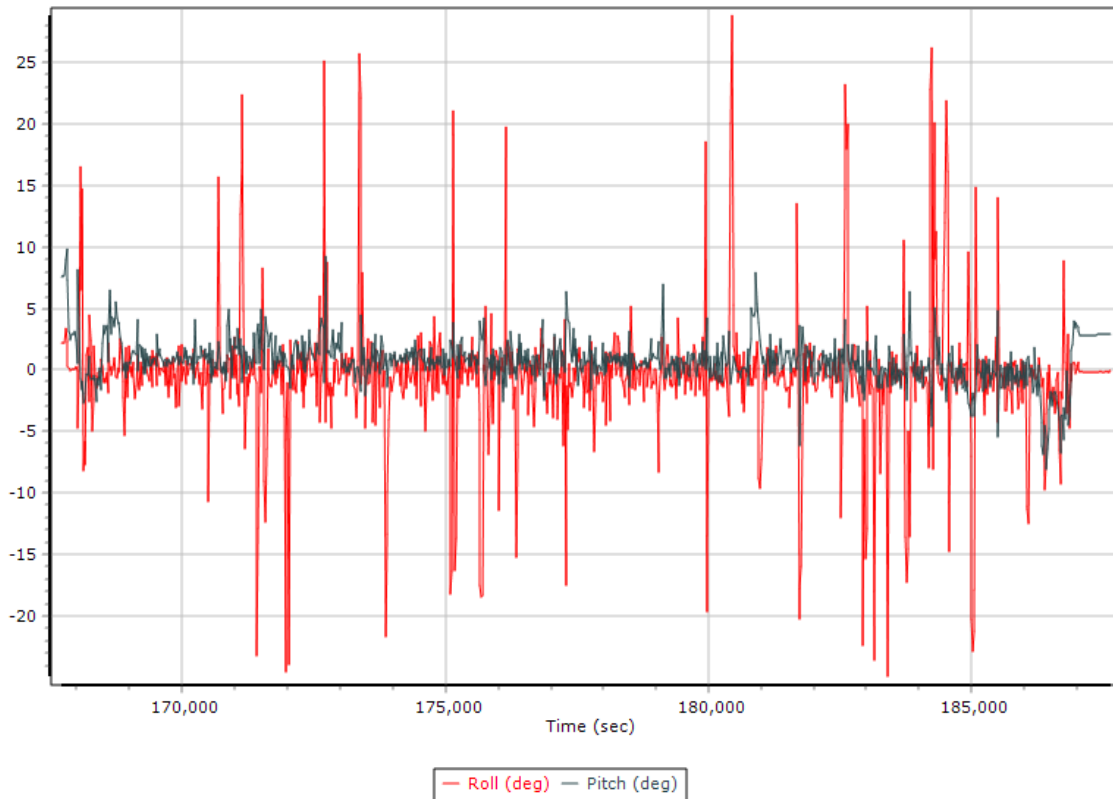
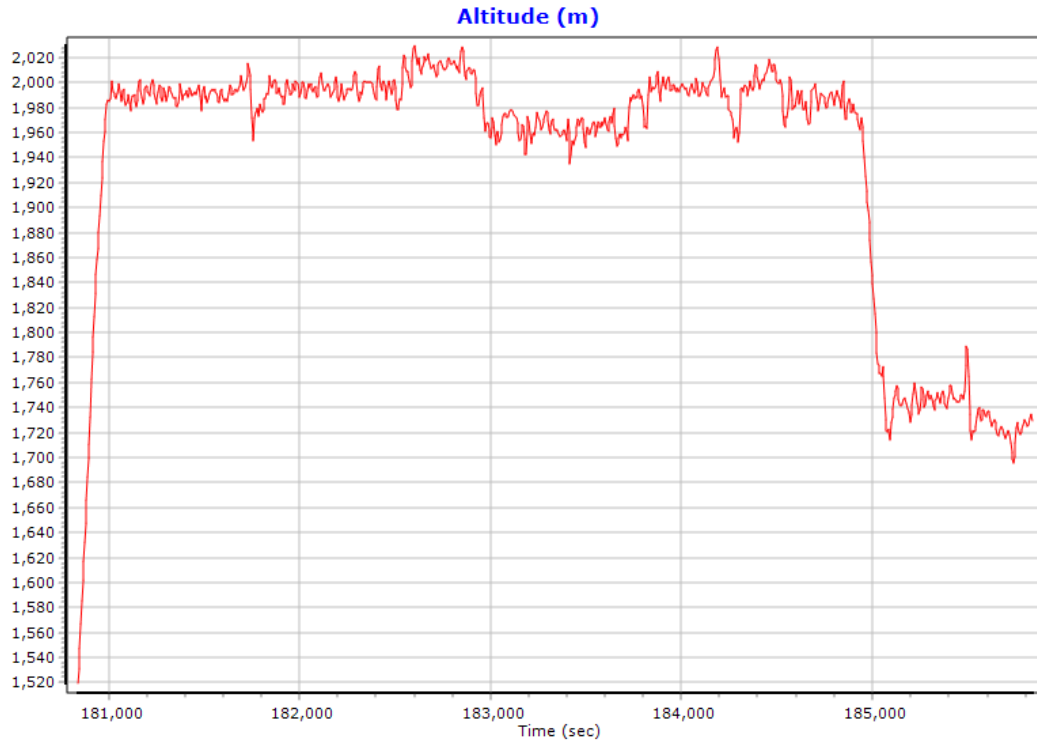


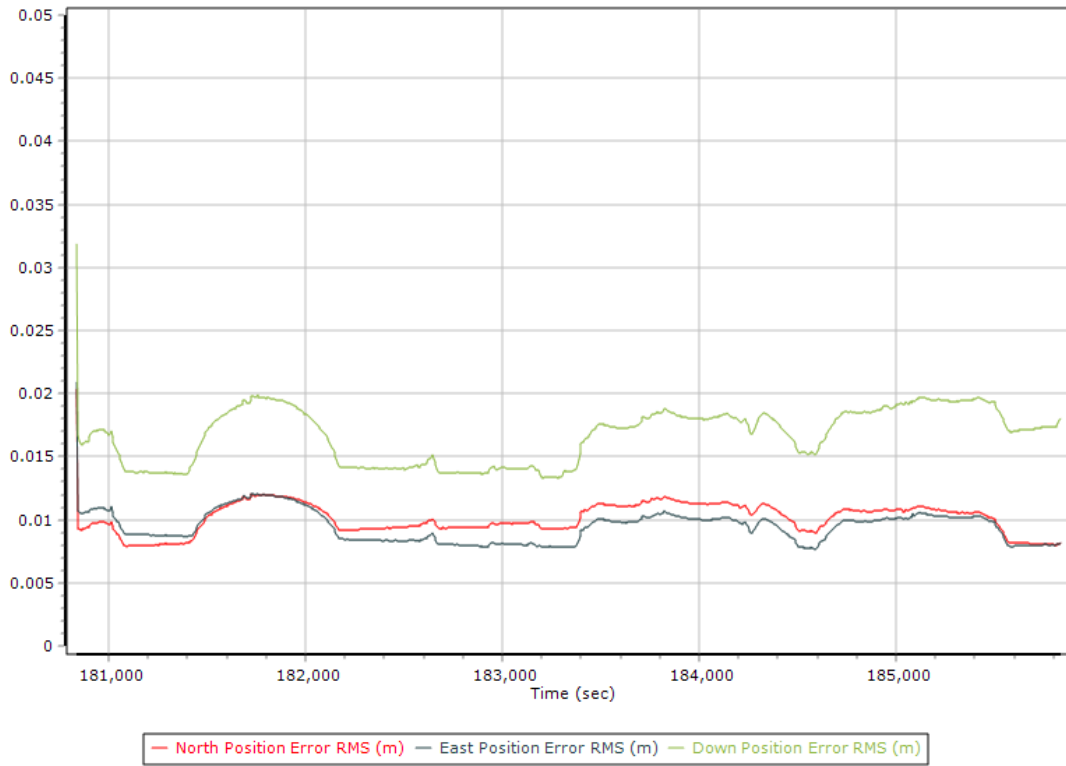
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	-0.034 m	X	0.000 deg
Y	-0.010 m	Y	0.000 deg
Z	-0.352 m	Z	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm		Aircraft to Stabilized Mount Mounting Angles	
X	-0.049 m	X	0.000 deg
Y	0.003 m	Y	0.000 deg
Z	-1.230 m	Z	0.000 deg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

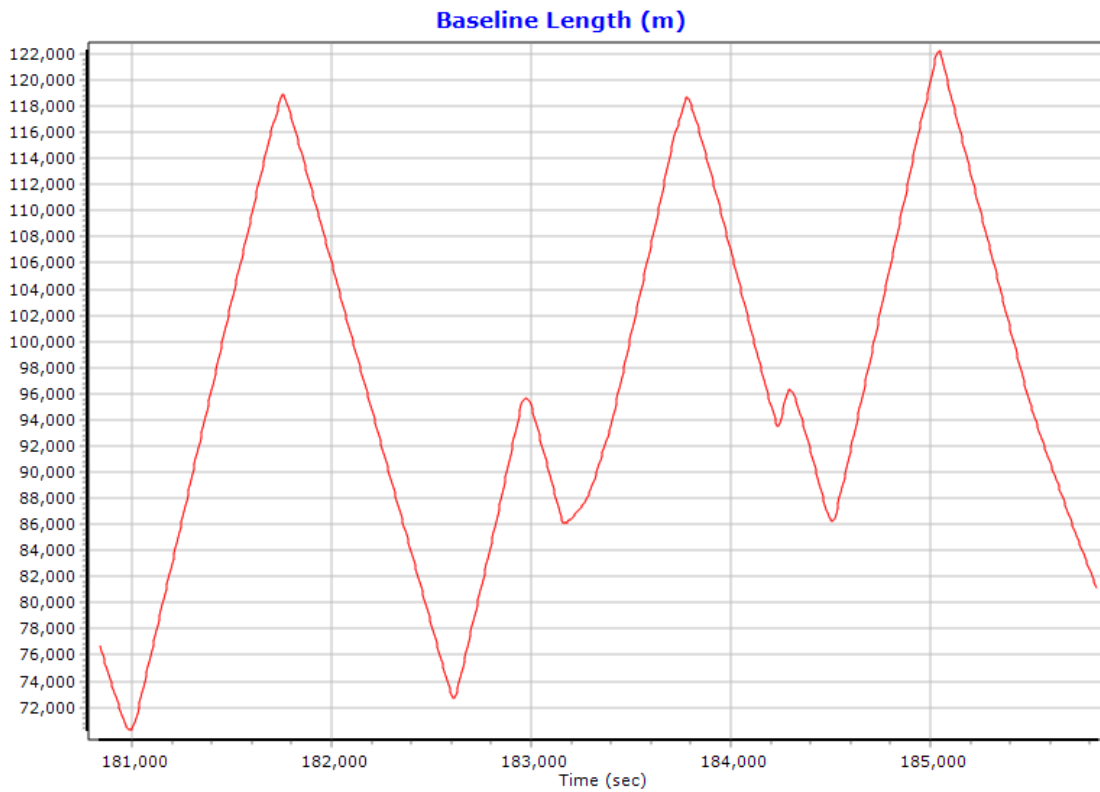
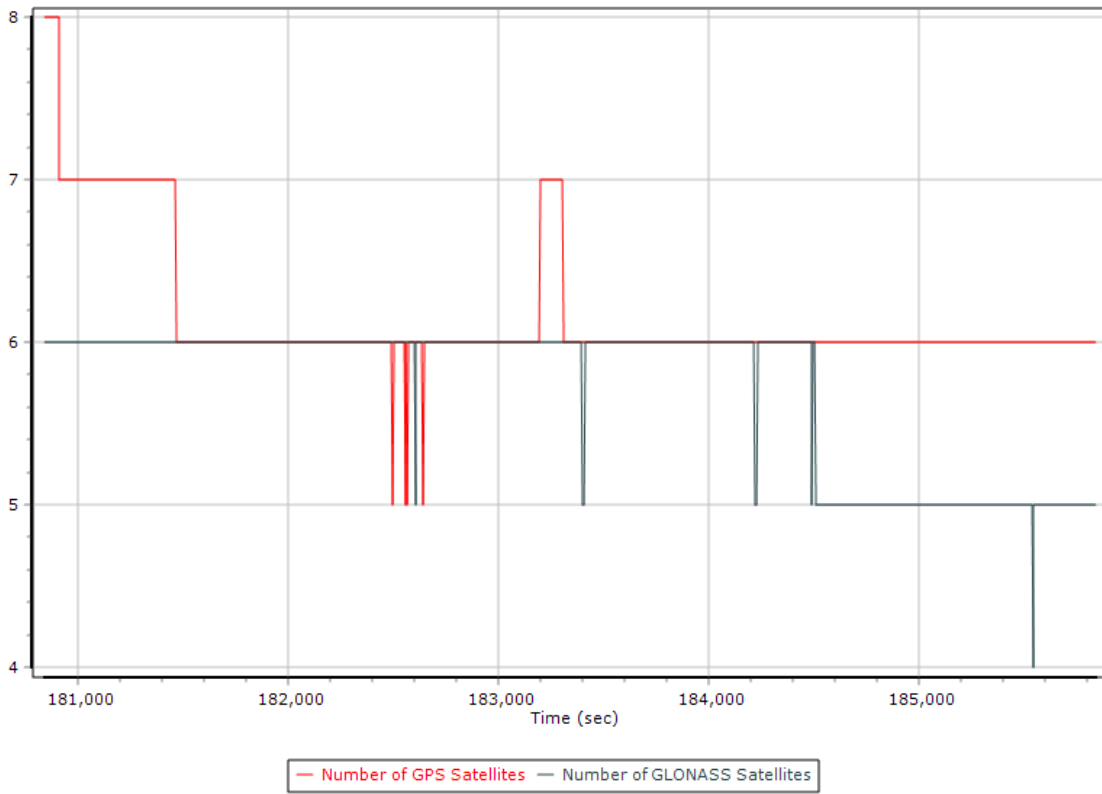
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

Timing	
Start	180835.797
End	185846.961
<input type="checkbox"/> Entire time interval	
<input checked="" type="checkbox"/> Seconds of start week	
UTC Offset	18.000

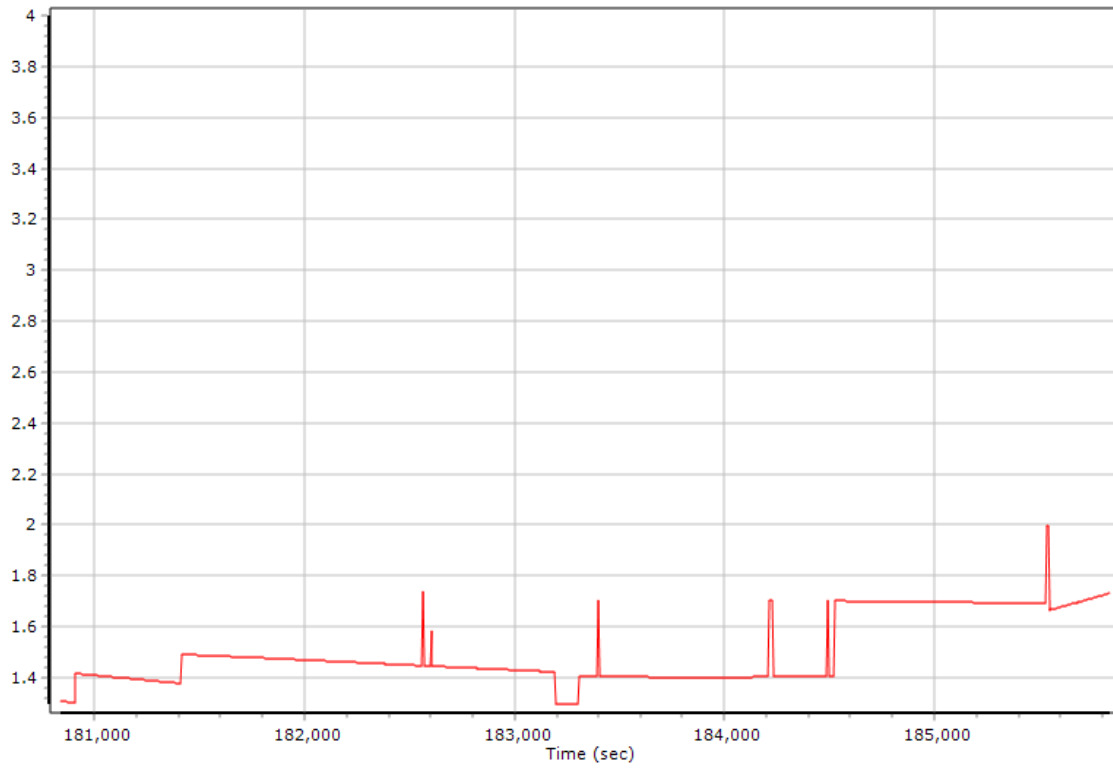
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



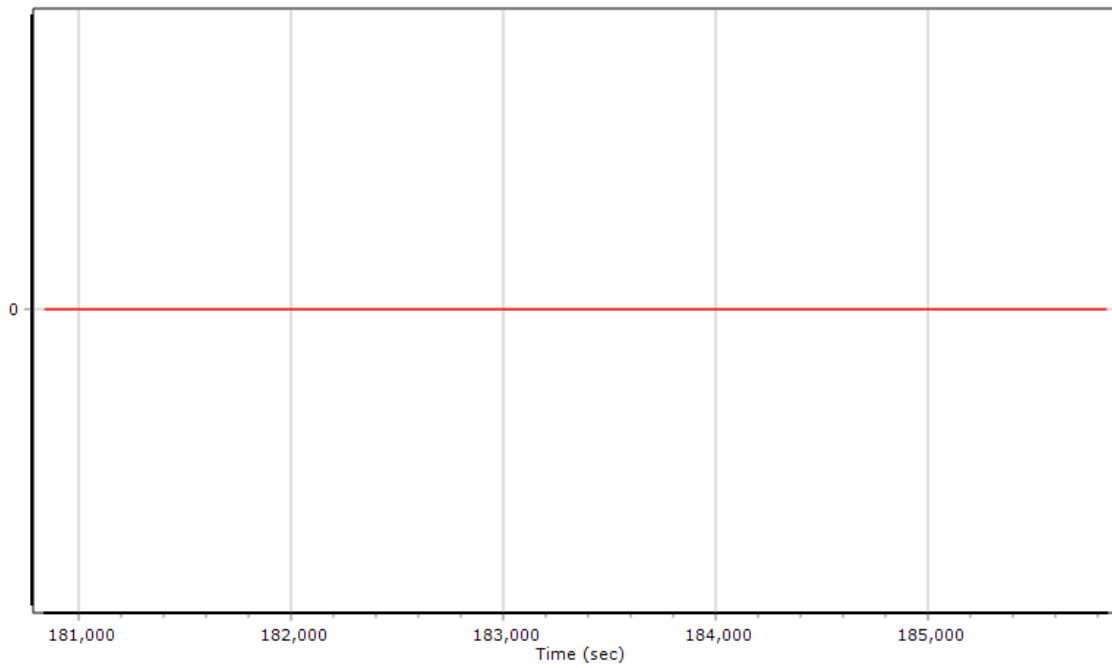




PDOP



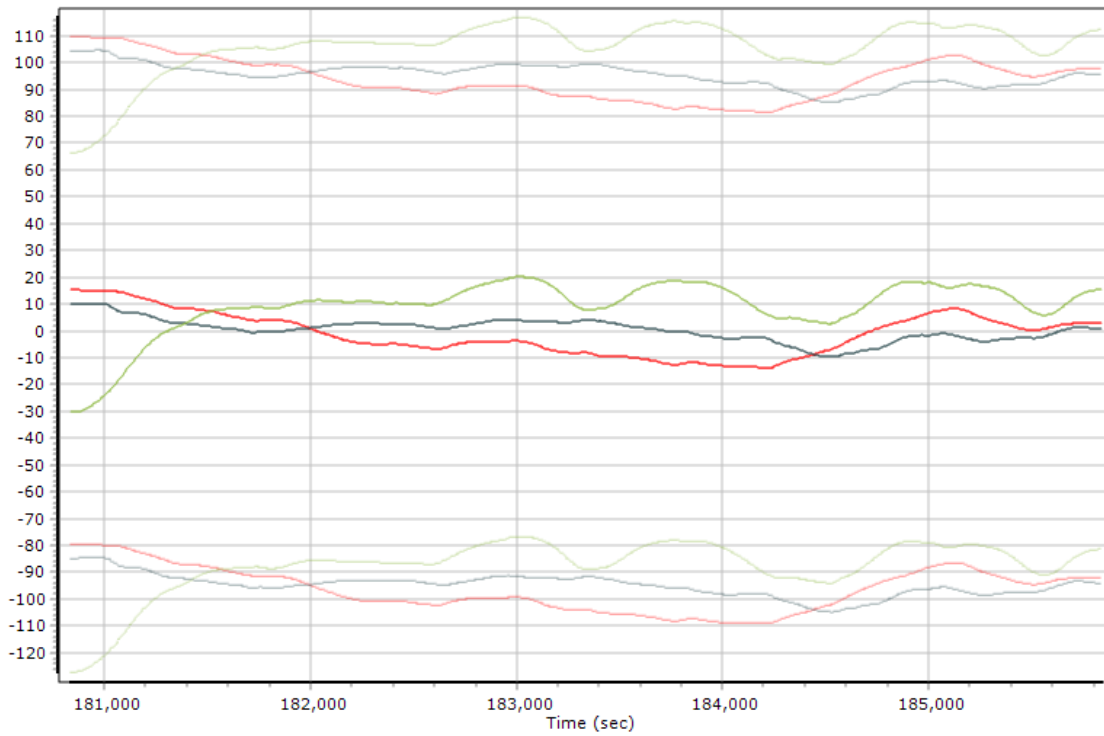
Processing Mode



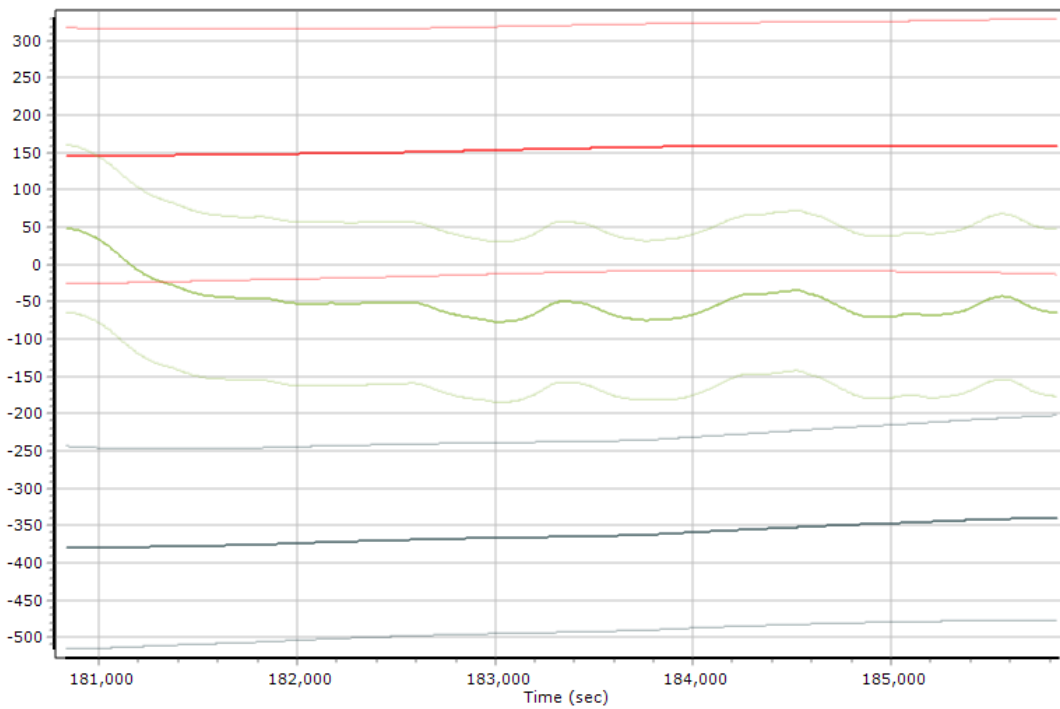
Forward Reverse

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

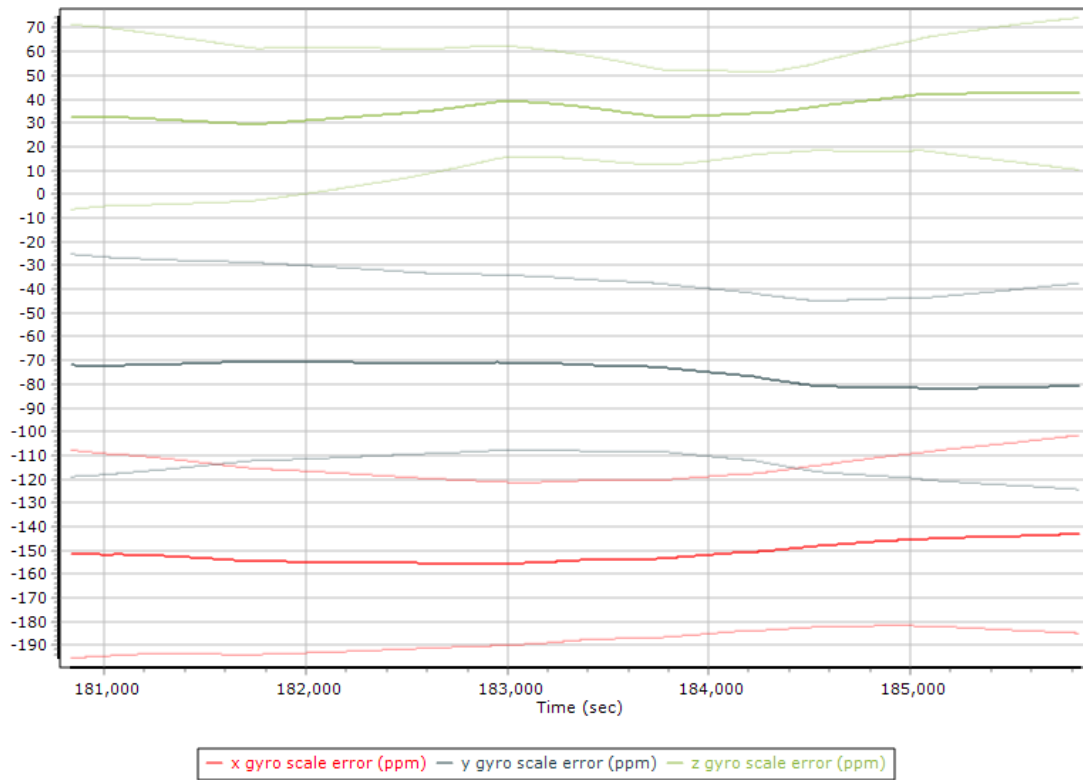
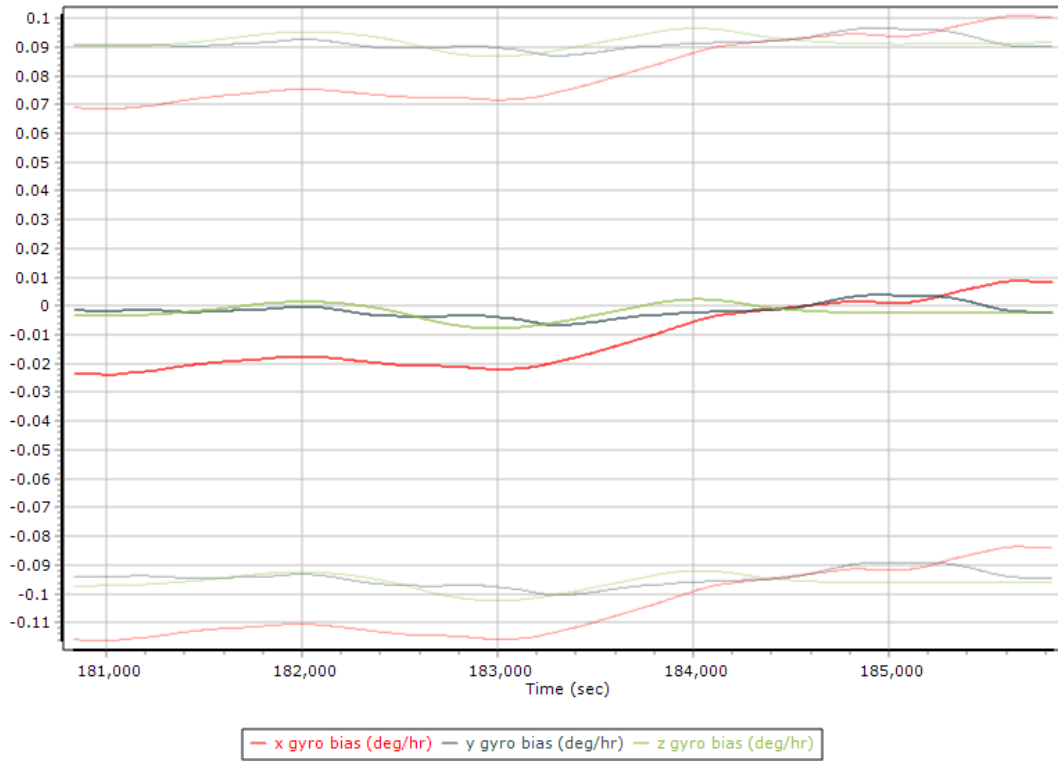
Sensor Errors



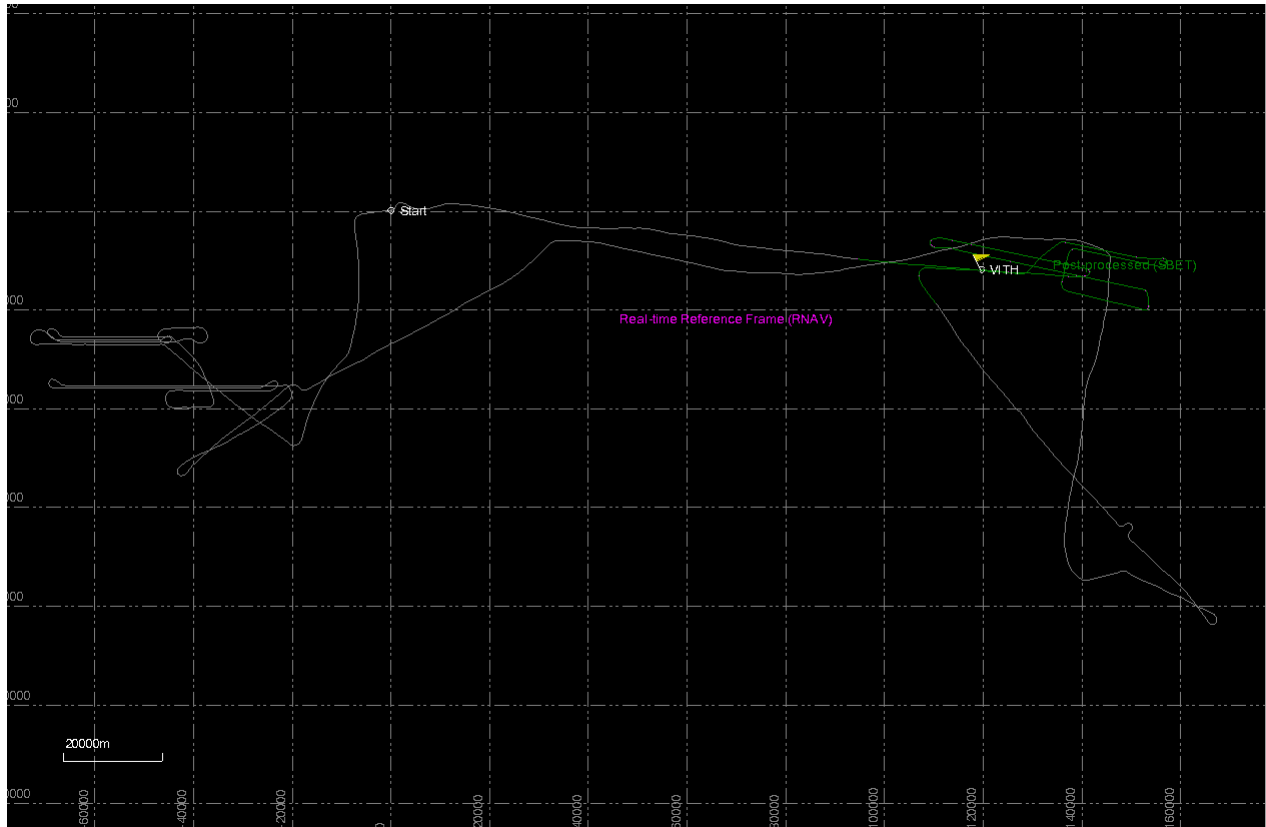
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



AZT18148B2



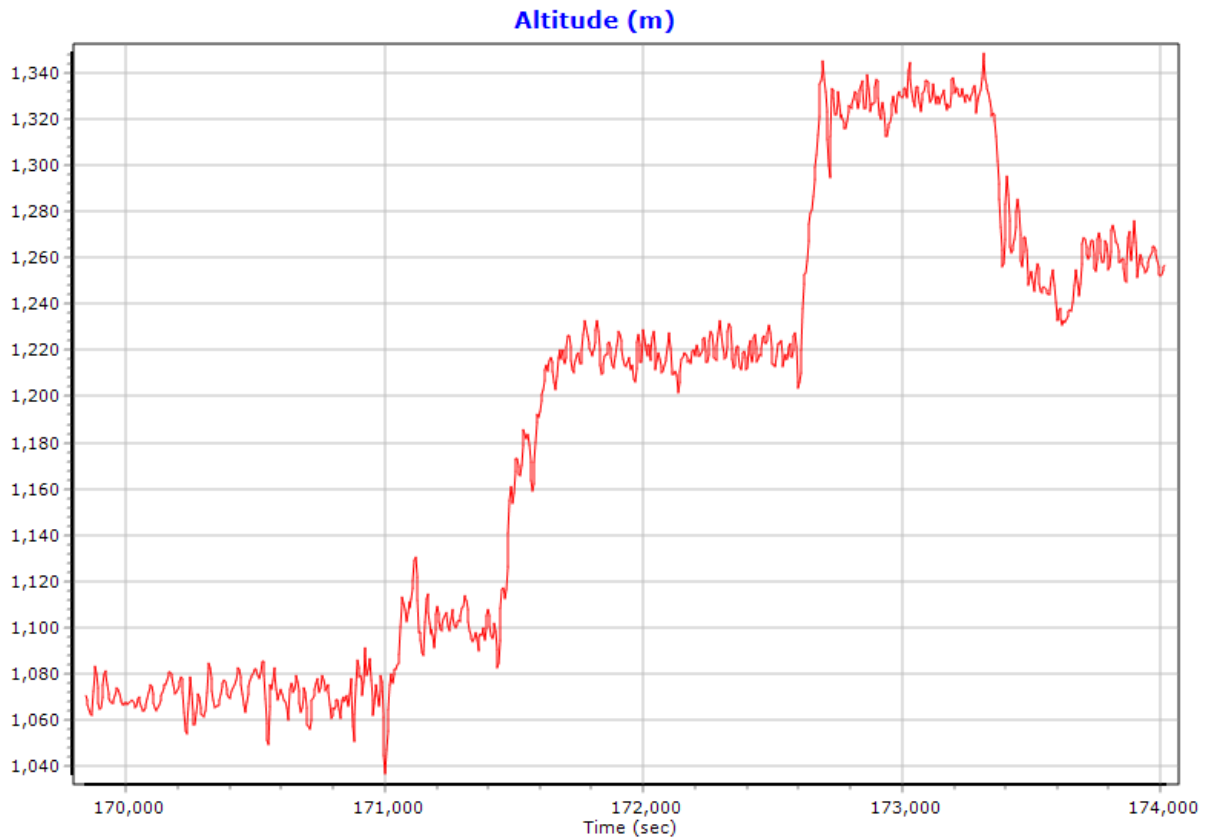
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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="3cm"/>		
	<3cm 10cm 50cm 1m 10m		

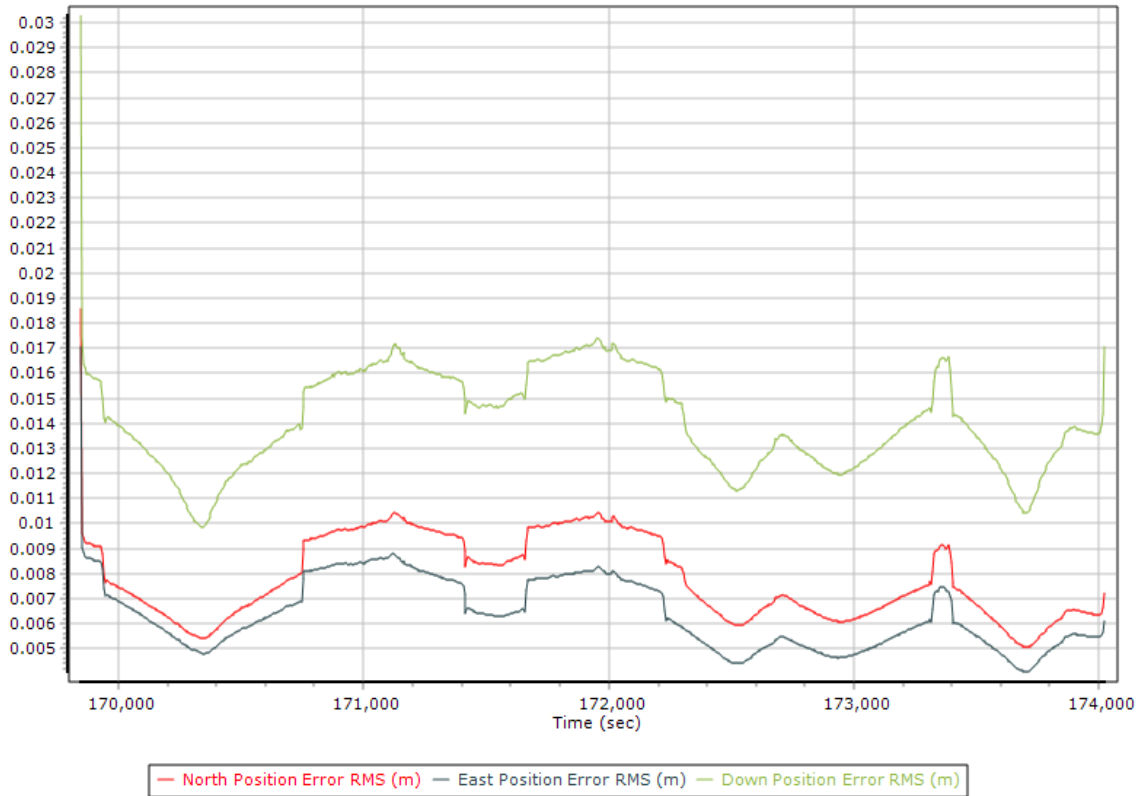
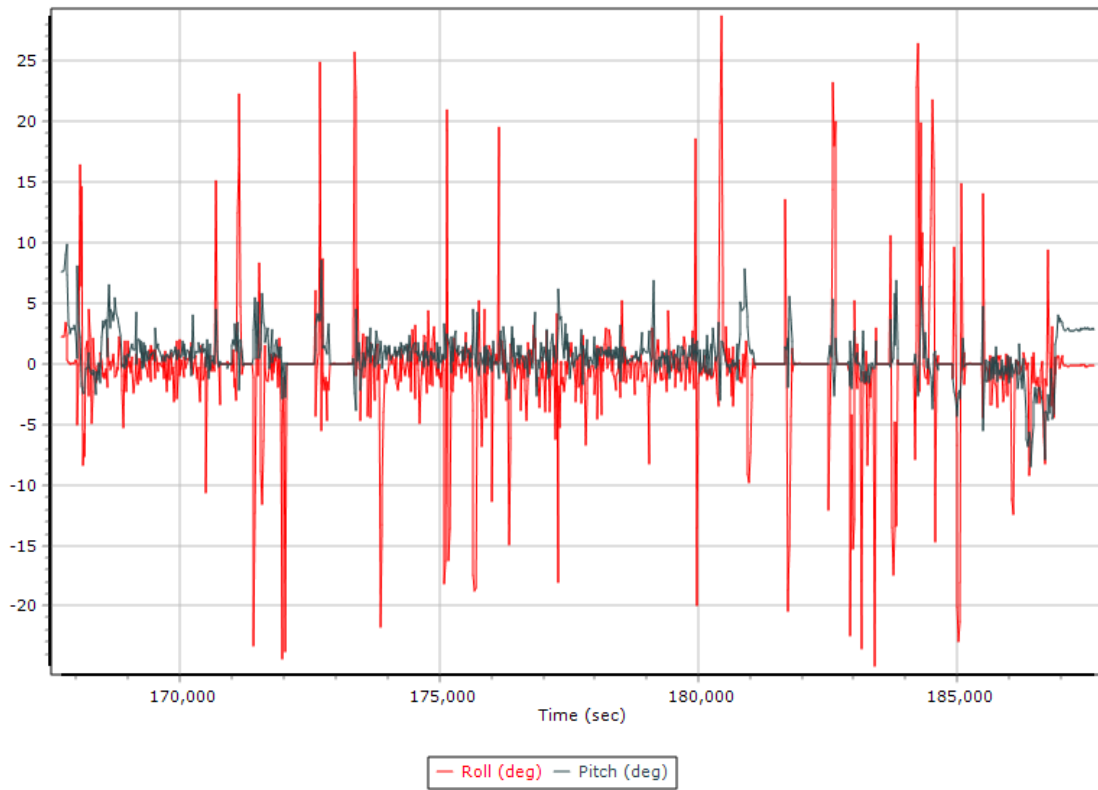
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

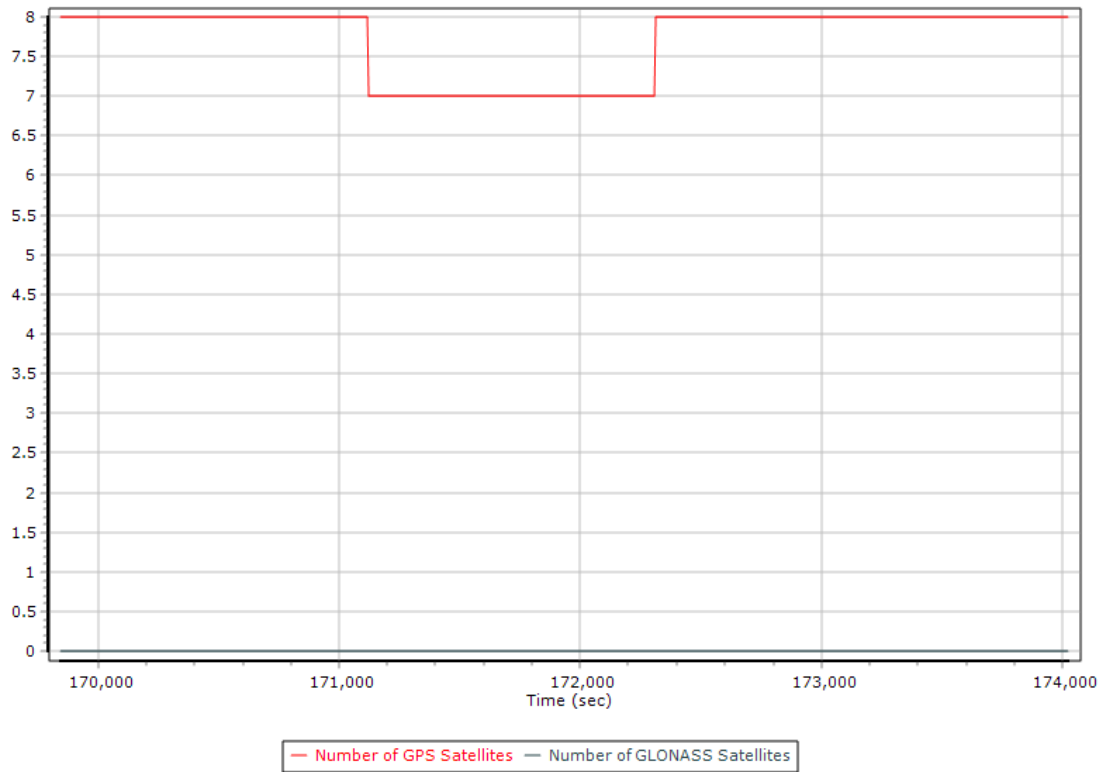
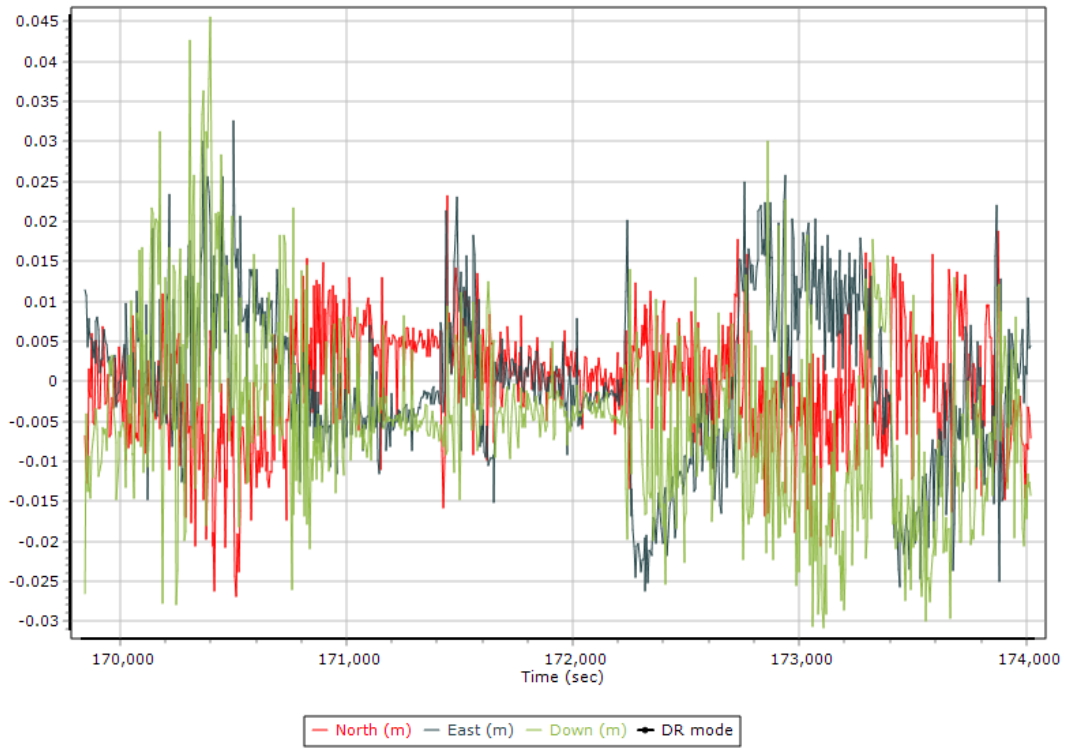
Timing

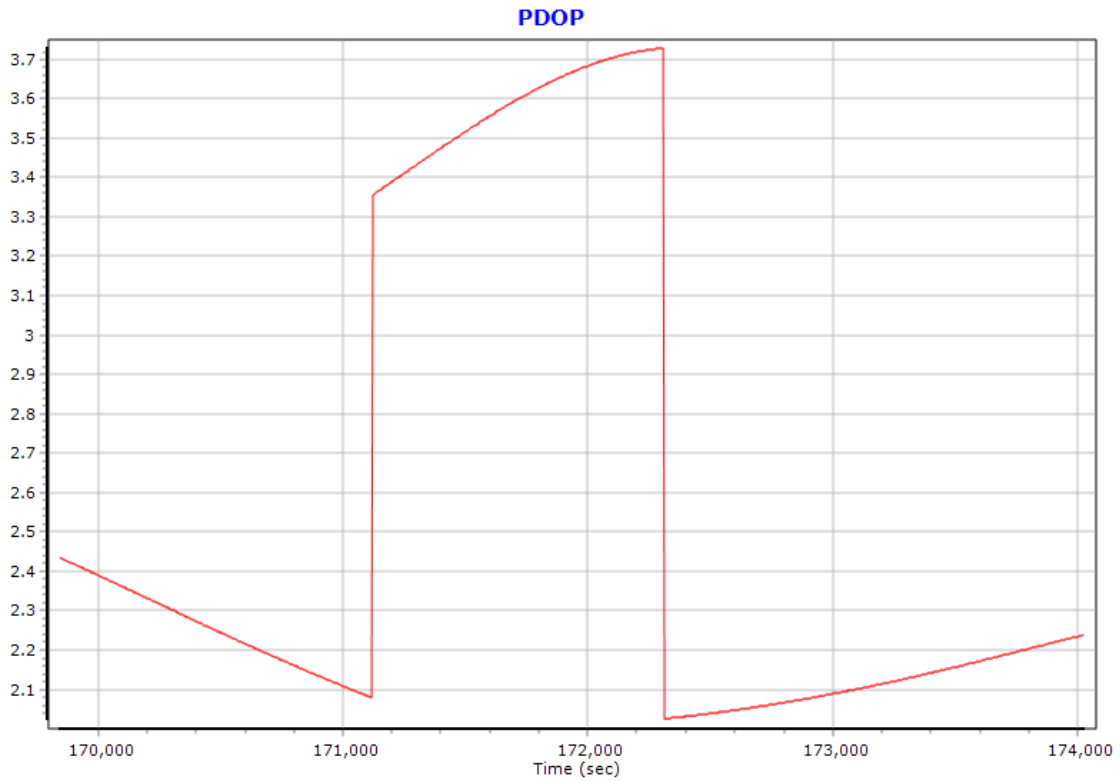
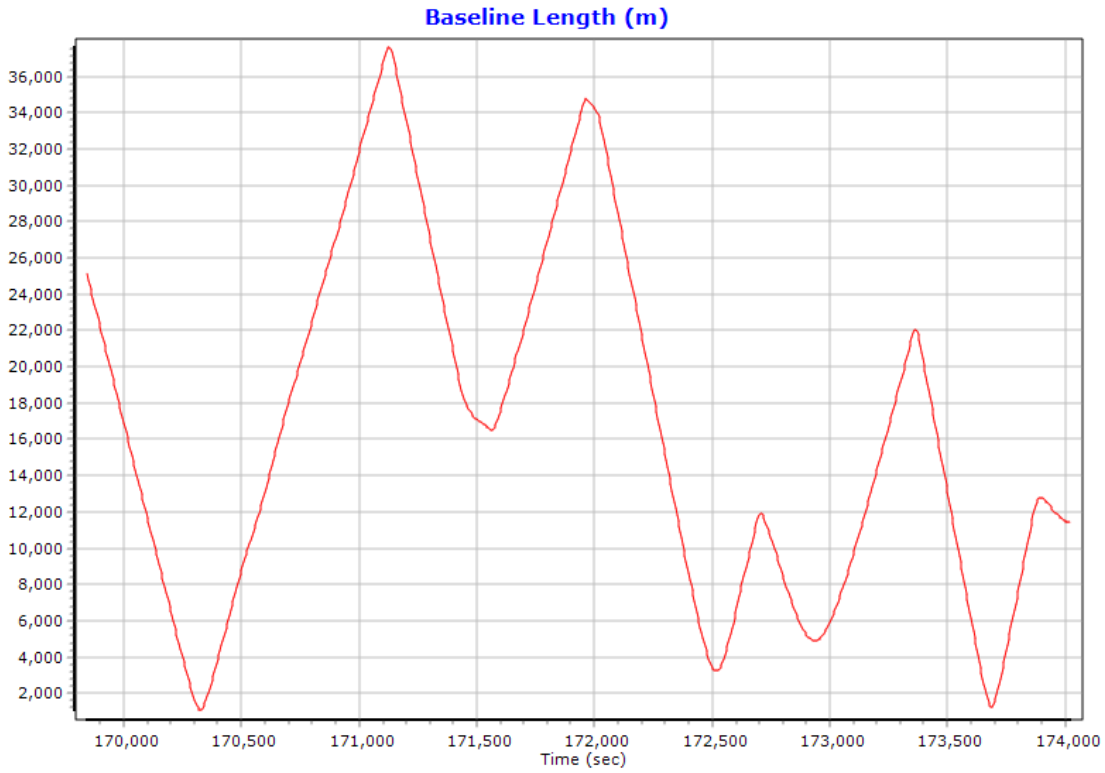
Start	169843.230	Data	Incr. (sec)	^
End	174024.209	Output Record	0.005000	
<input type="checkbox"/> Entire time interval		IMU	0.005000	
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000	v

UTC Offset 18.000

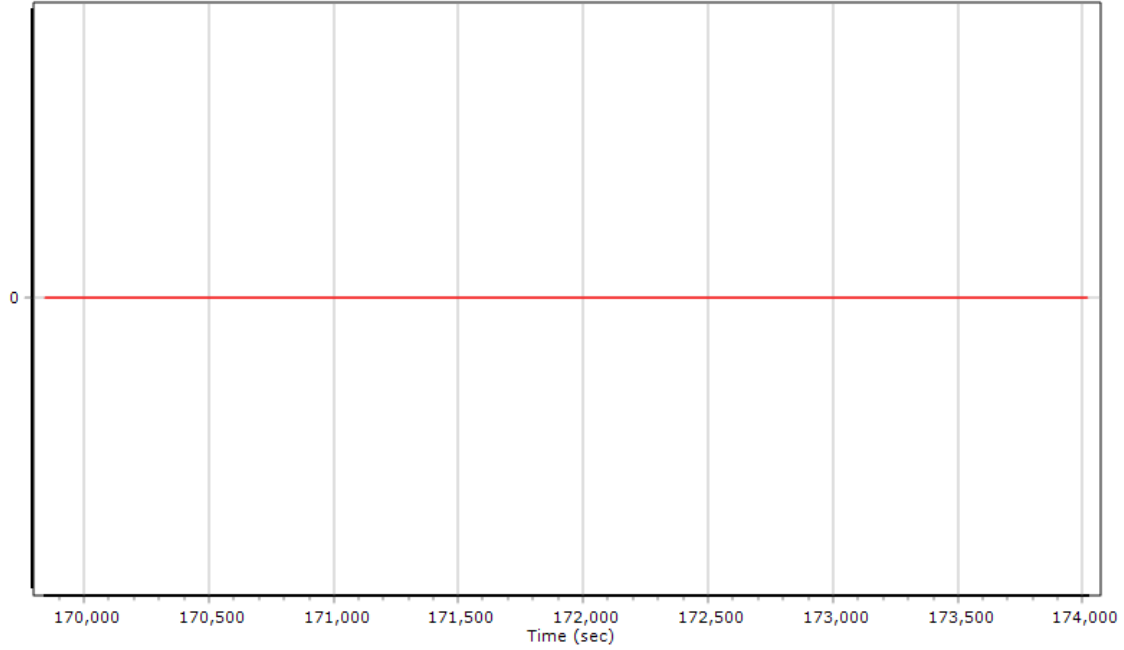








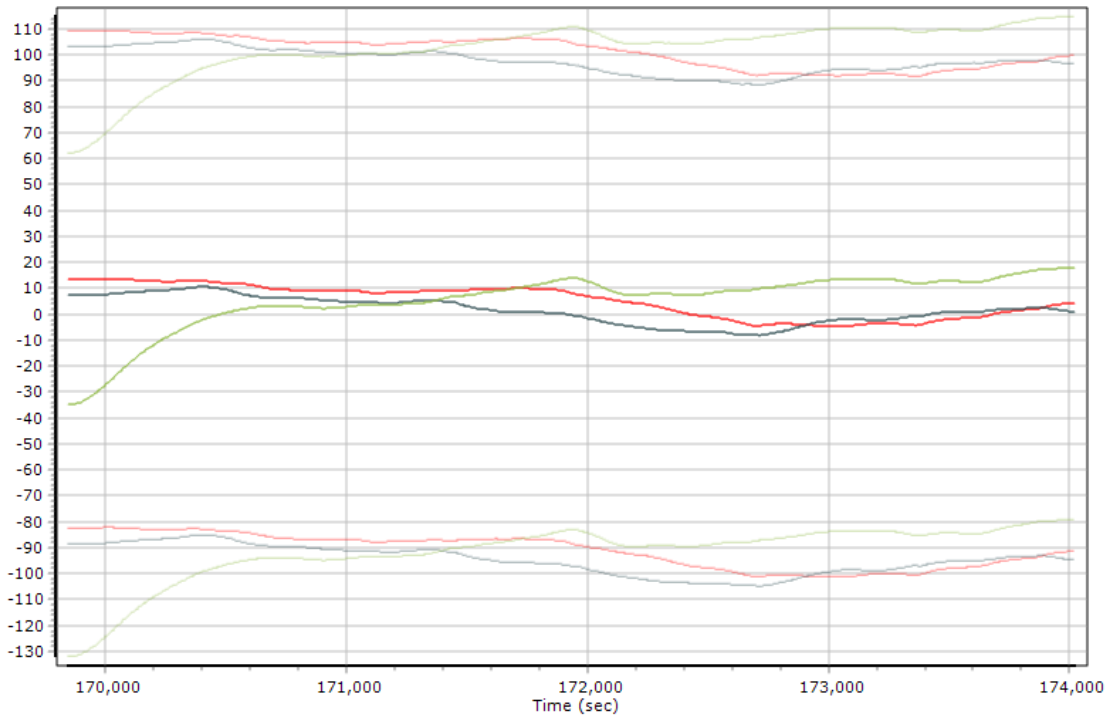
Processing Mode



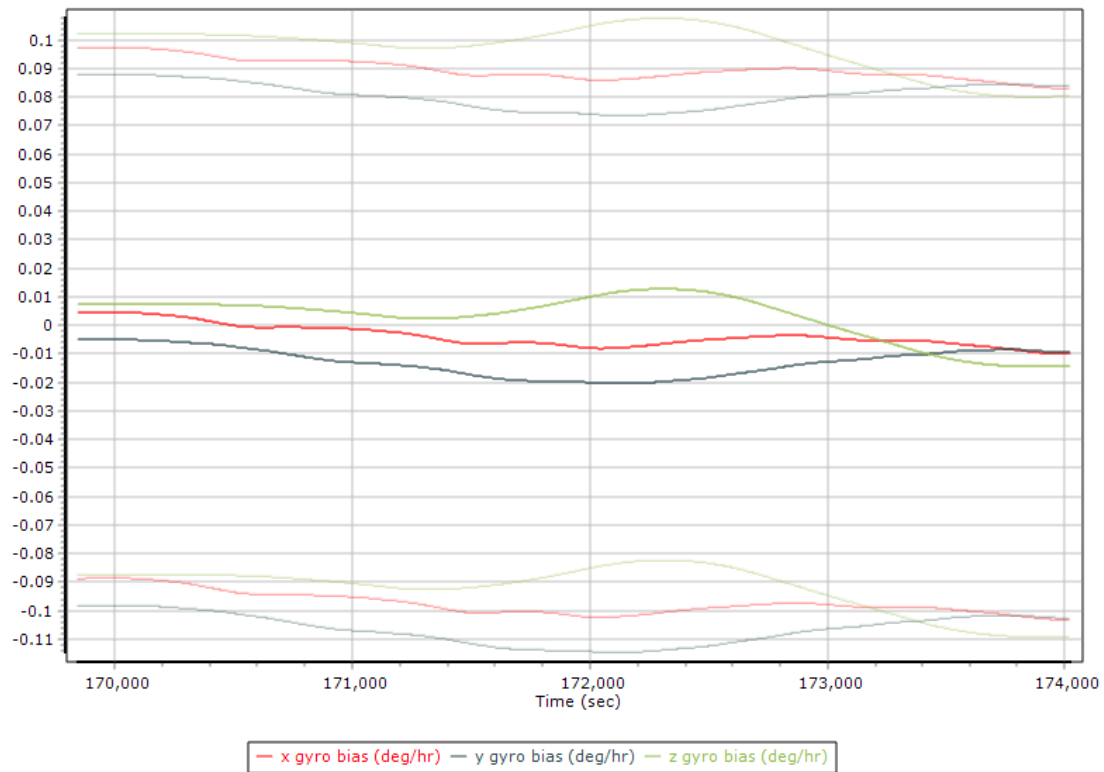
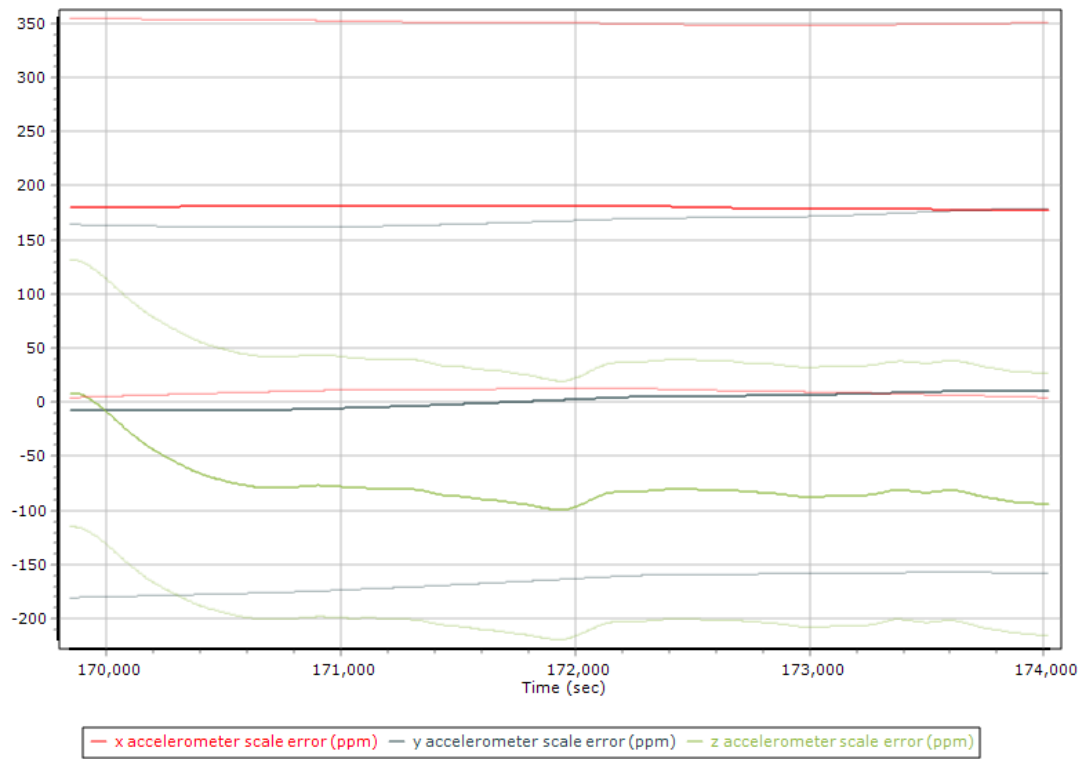
Forward Reverse

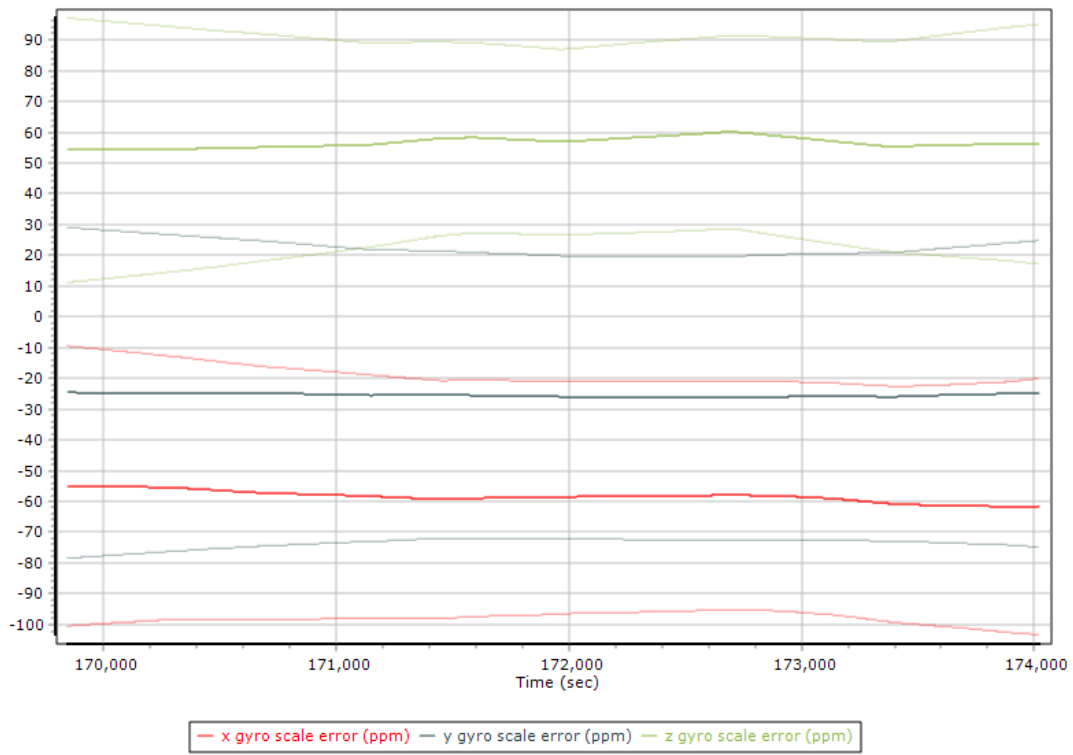
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

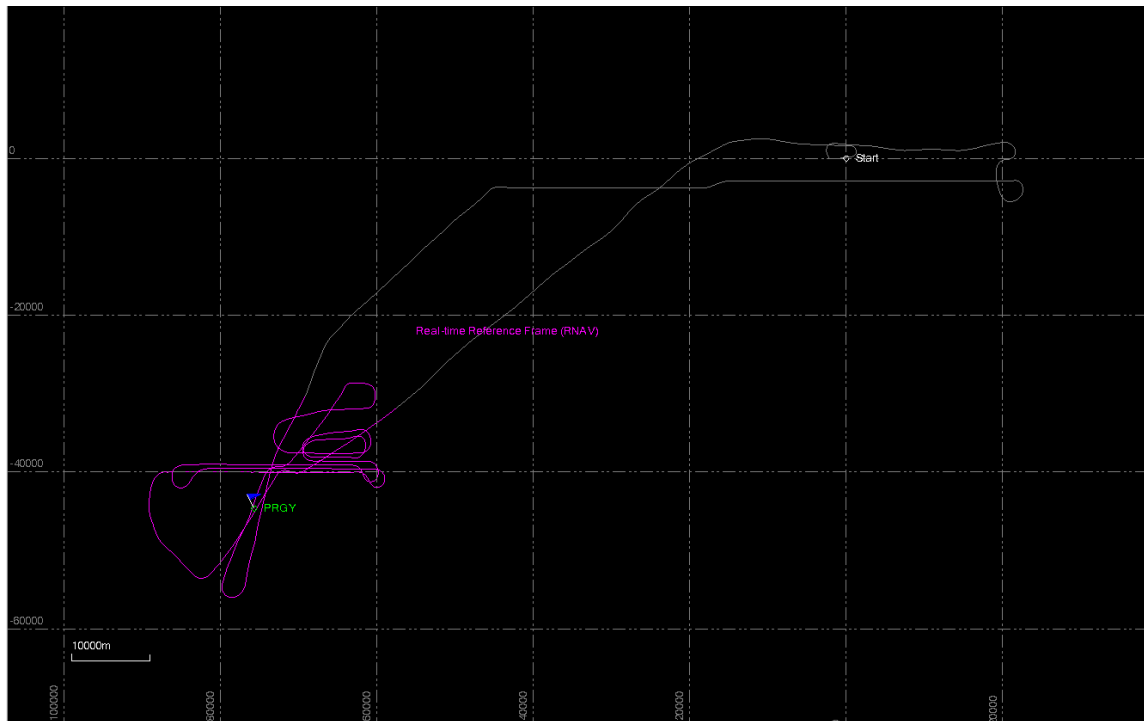


— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)





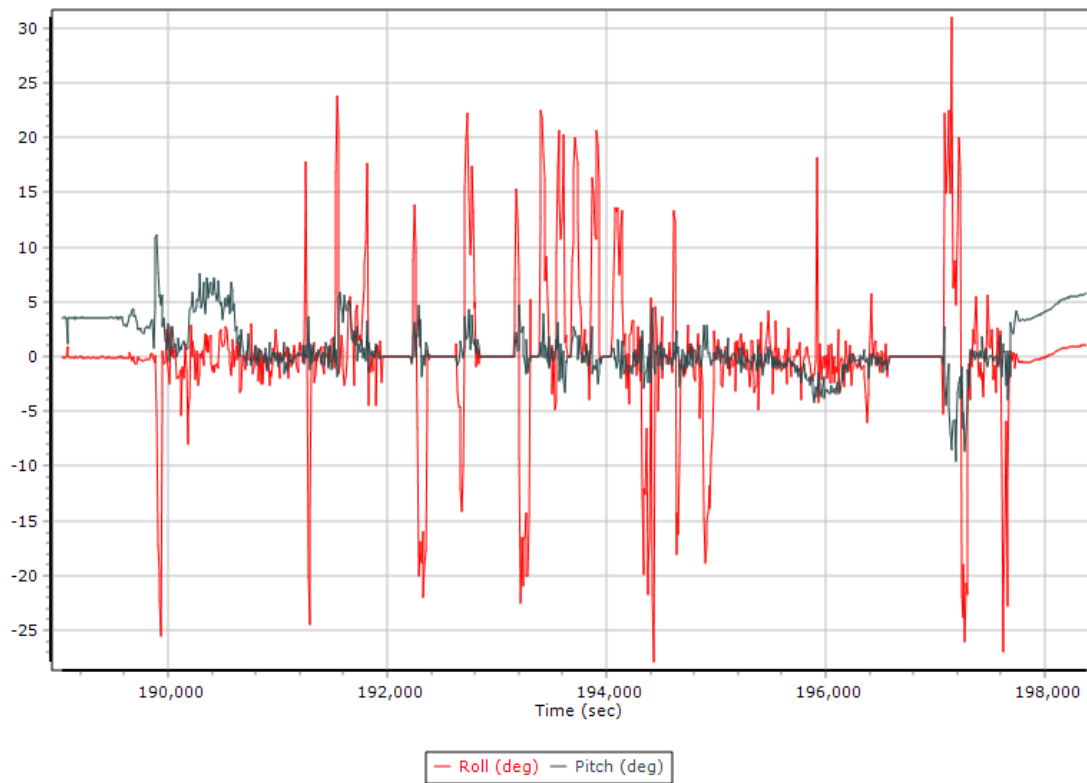
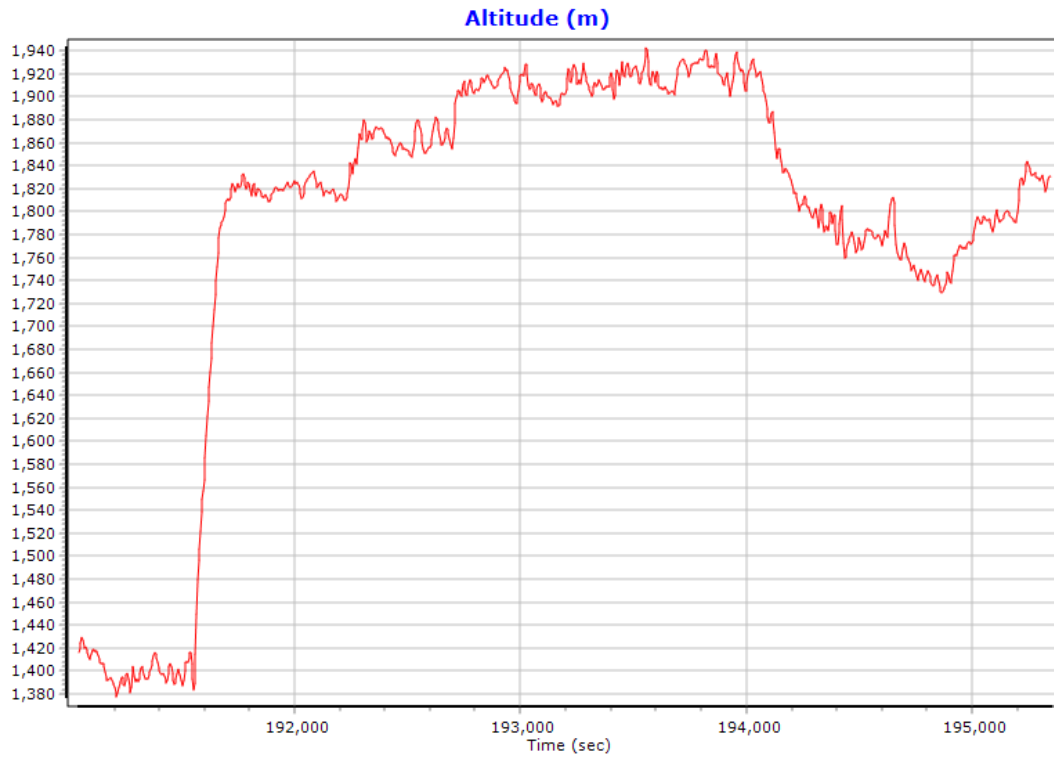
AZT18149A

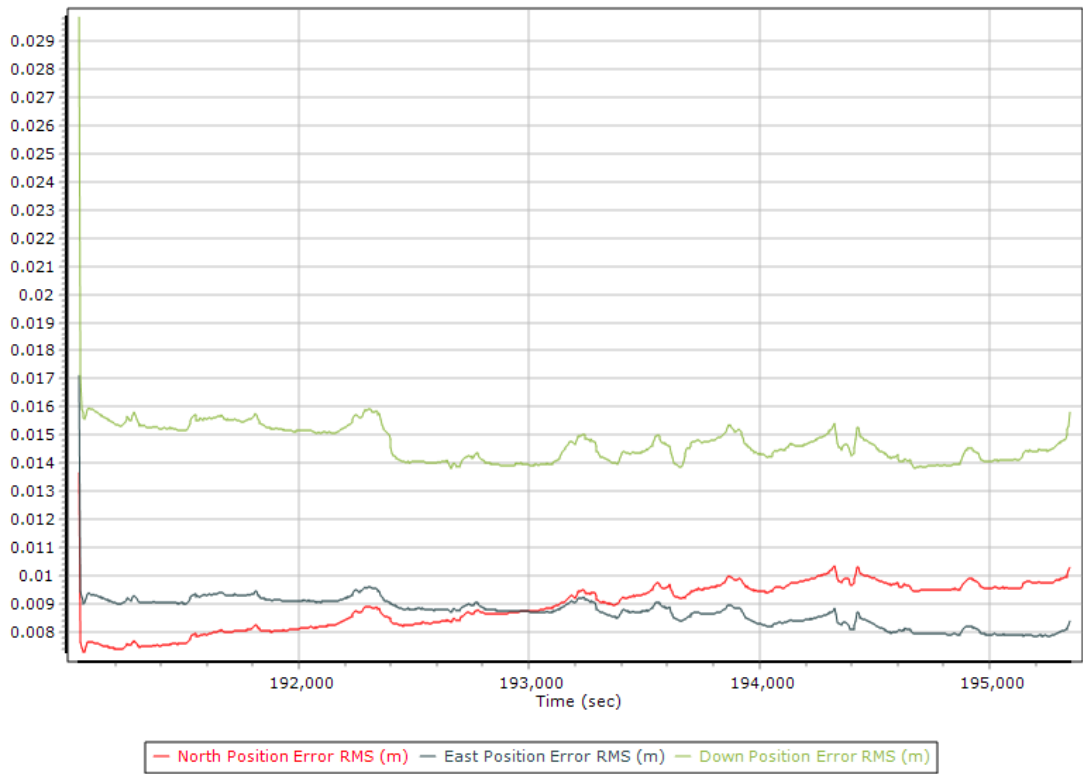


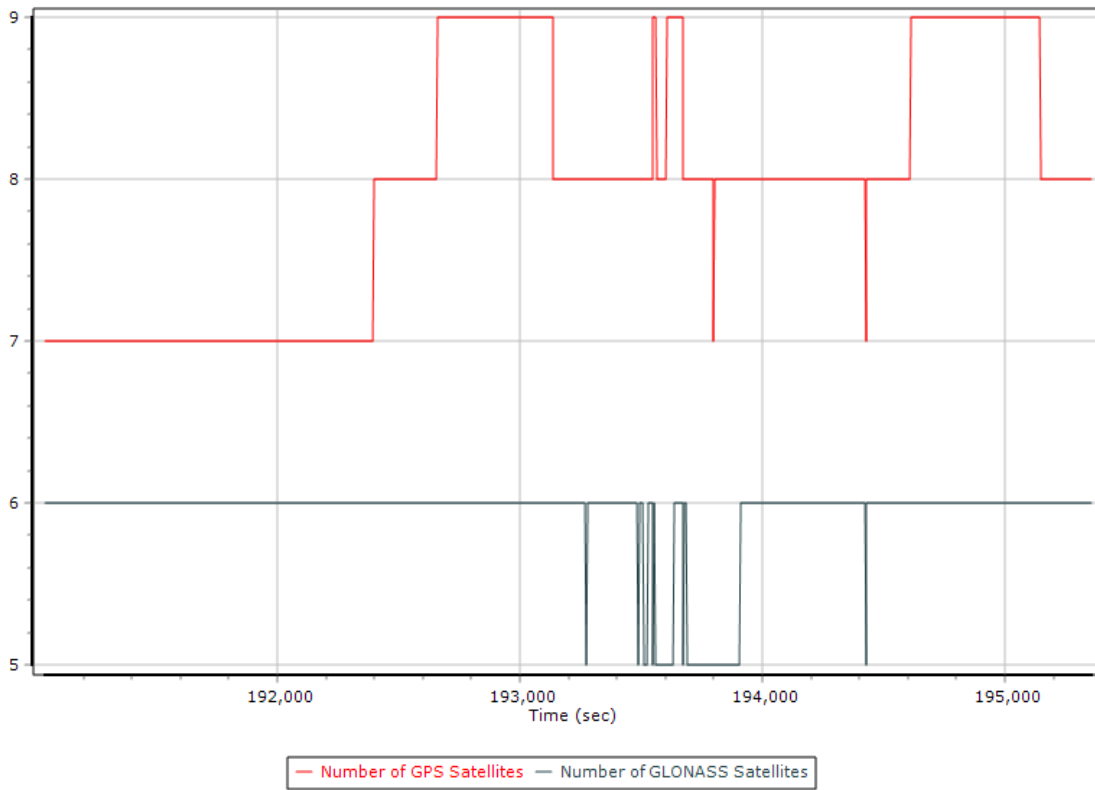
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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="0.3"/>		
	<3cm 10cm 50cm 1m 10m		

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

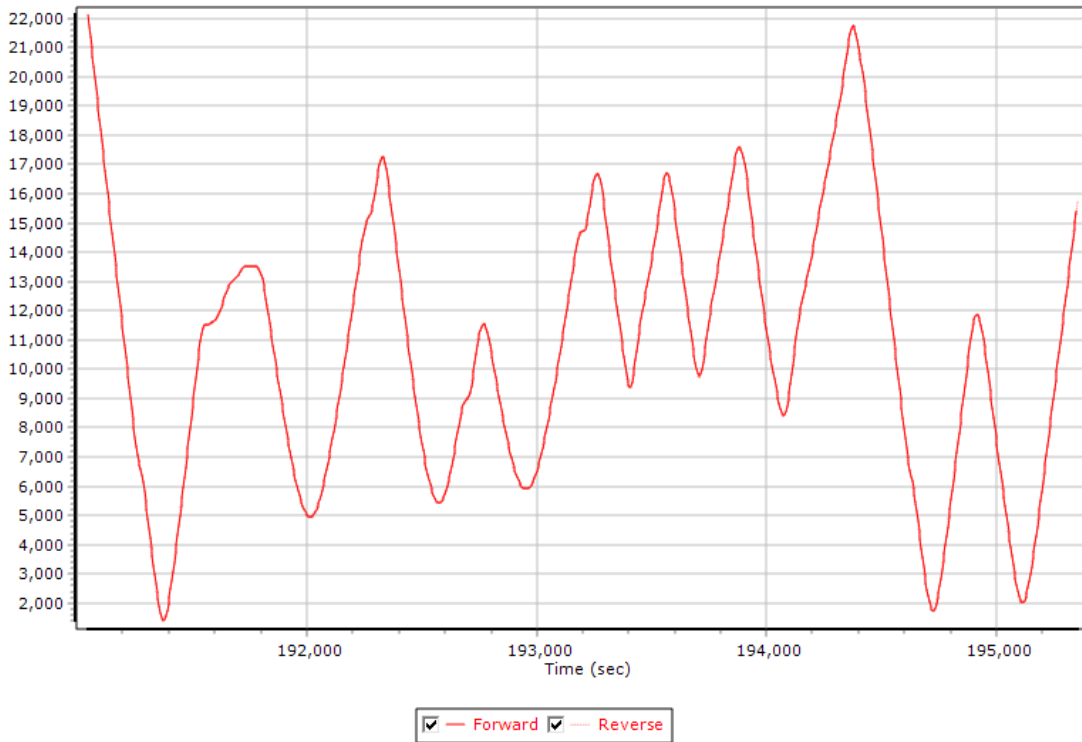
Timing									
Start	<input type="text" value="191041.944"/>								
End	<input type="text" value="195357.951"/>								
<input type="checkbox"/> Entire time interval									
<input checked="" type="checkbox"/> Seconds of start week									
UTC Offset	<input type="text" value="18.000"/>								
<table border="1"><thead><tr><th>Data</th><th>Incr. (sec)</th></tr></thead><tbody><tr><td>Output Record</td><td>0.005000</td></tr><tr><td>IMU</td><td>0.005000</td></tr><tr><td>Primary GNSS</td><td>1.000000</td></tr></tbody></table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000	
Data	Incr. (sec)								
Output Record	0.005000								
IMU	0.005000								
Primary GNSS	1.000000								

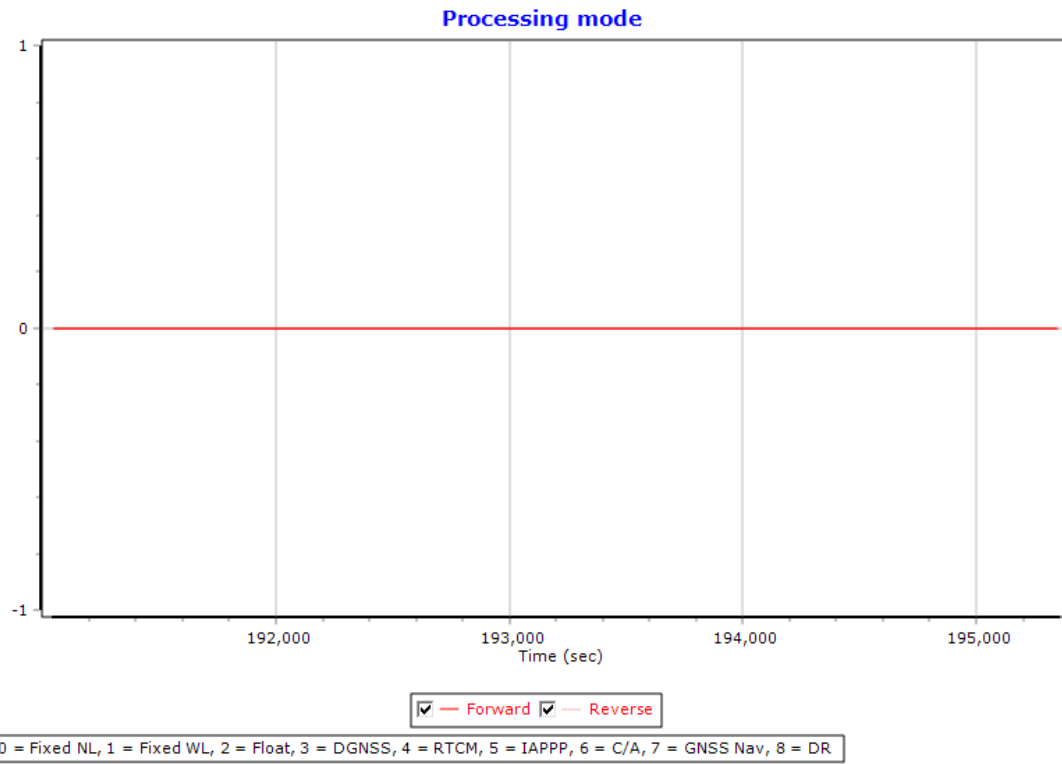
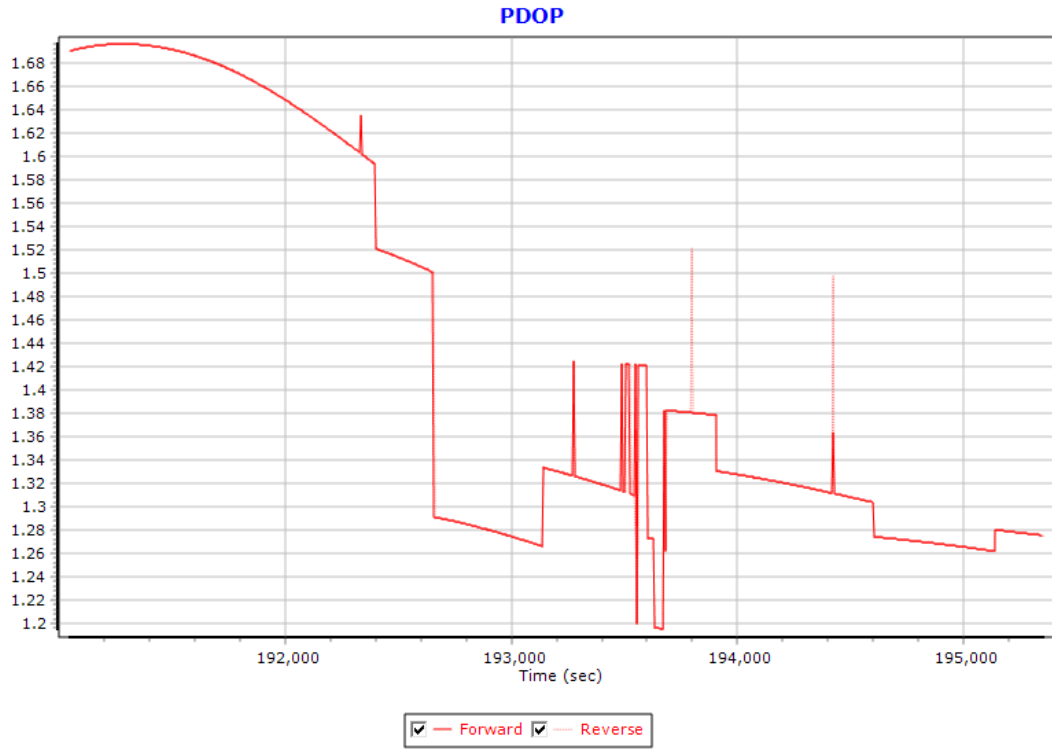




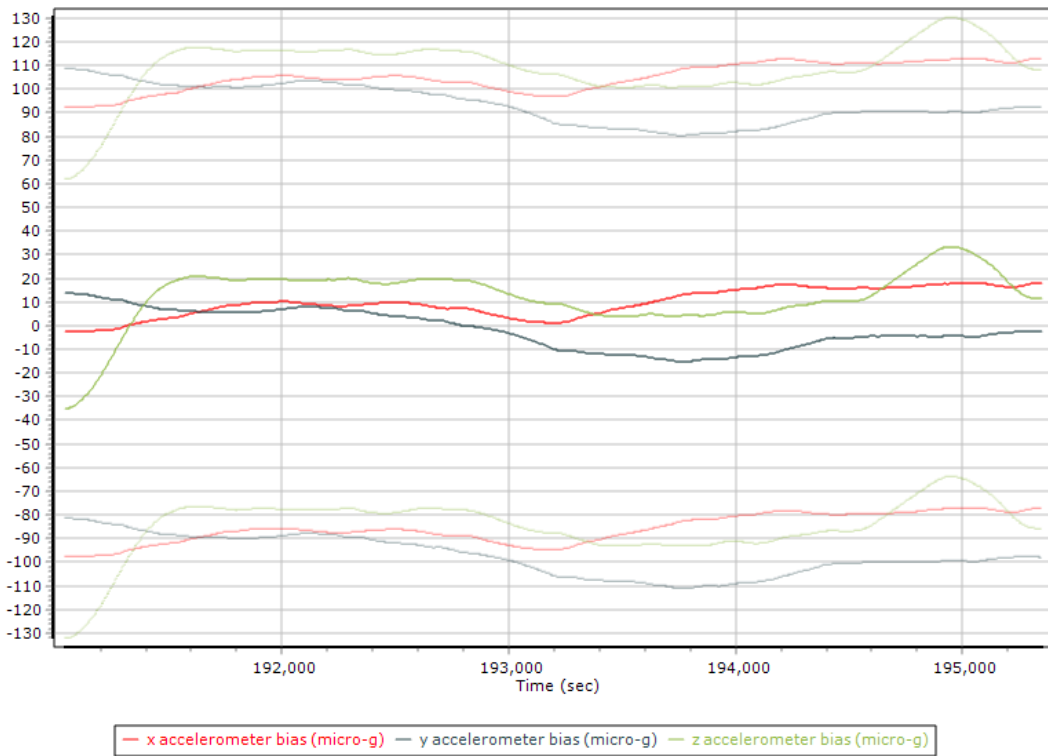
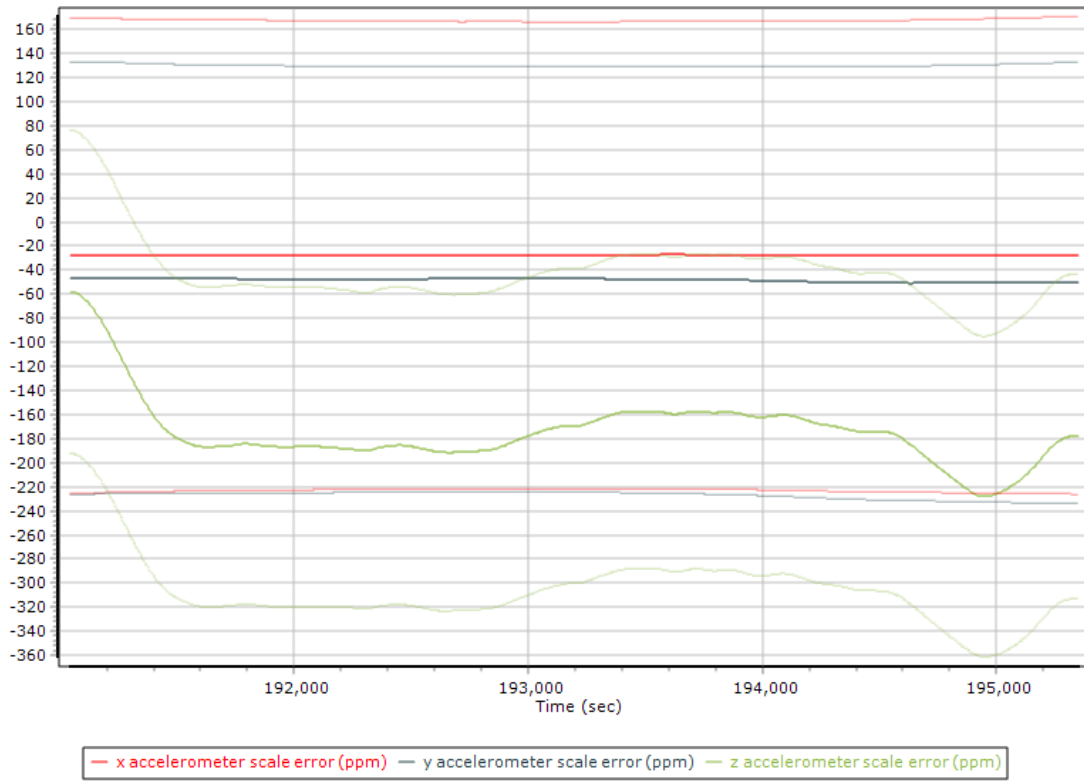


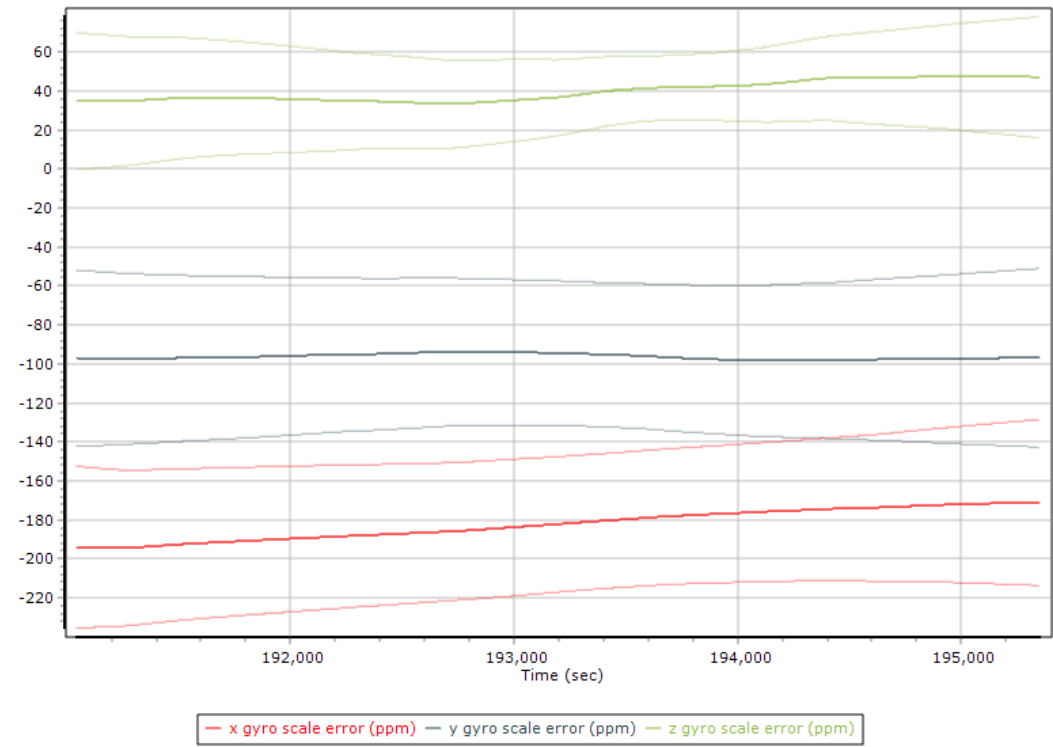
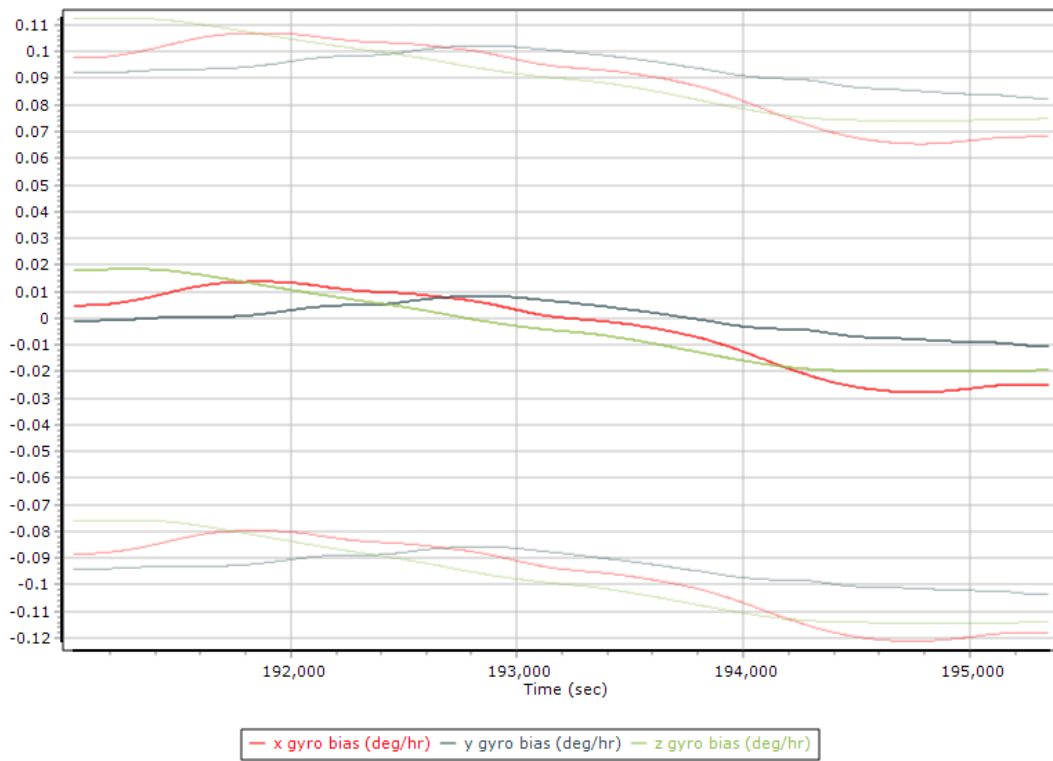
Baseline Length (m)



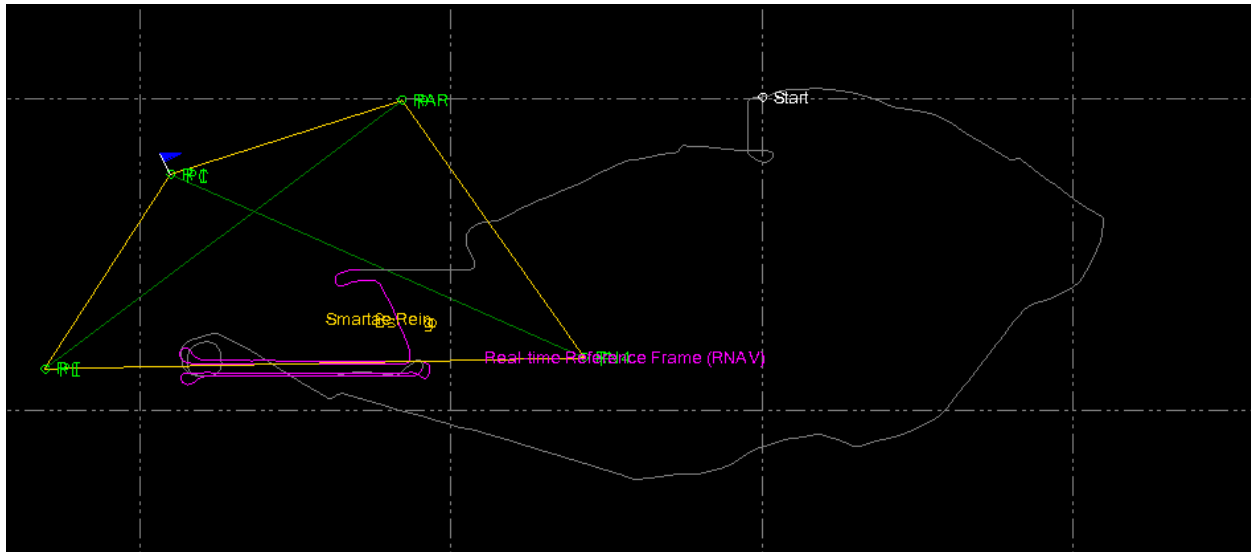


Sensor Errors





AZT18149B



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

Arm	
X	<input type="text" value="-0.049 m"/>
Y	<input type="text" value="0.003 m"/>
Z	<input type="text" value="-0.738 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

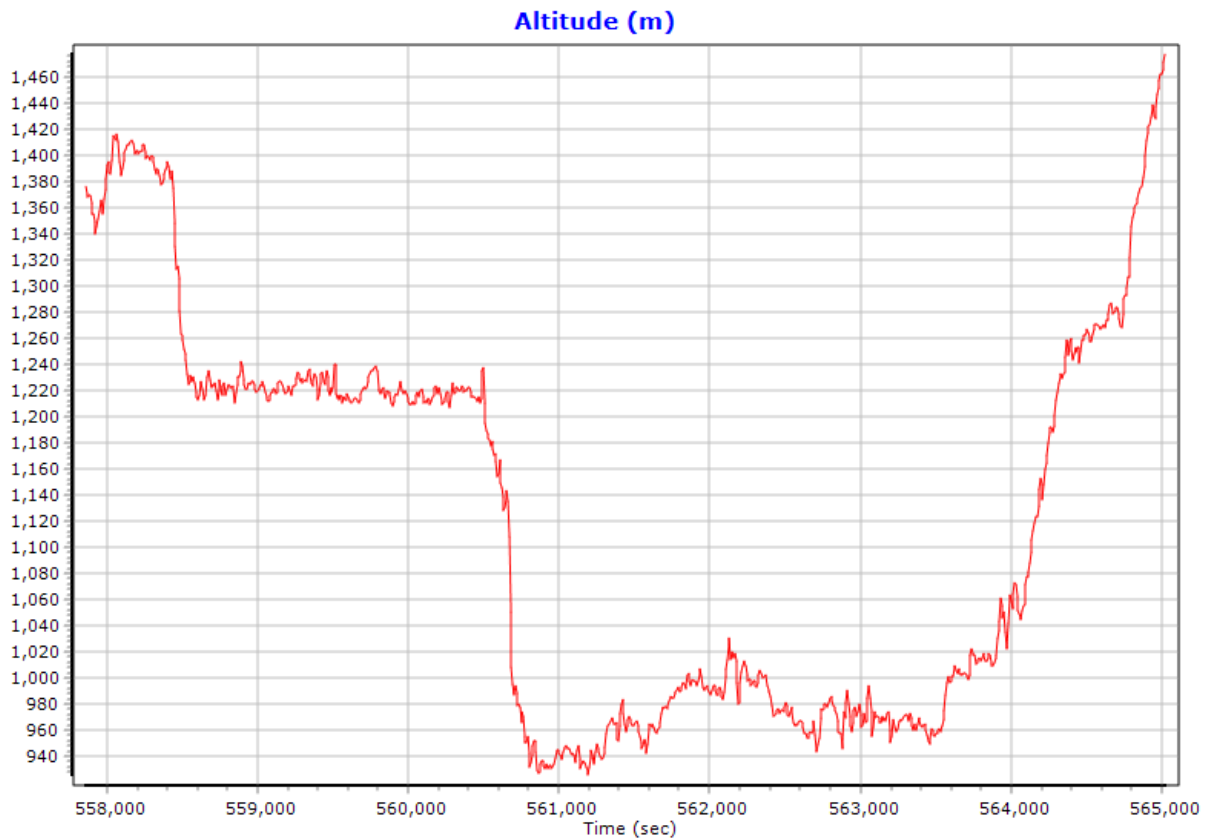
<3cm 10cm 50cm 1m 10m

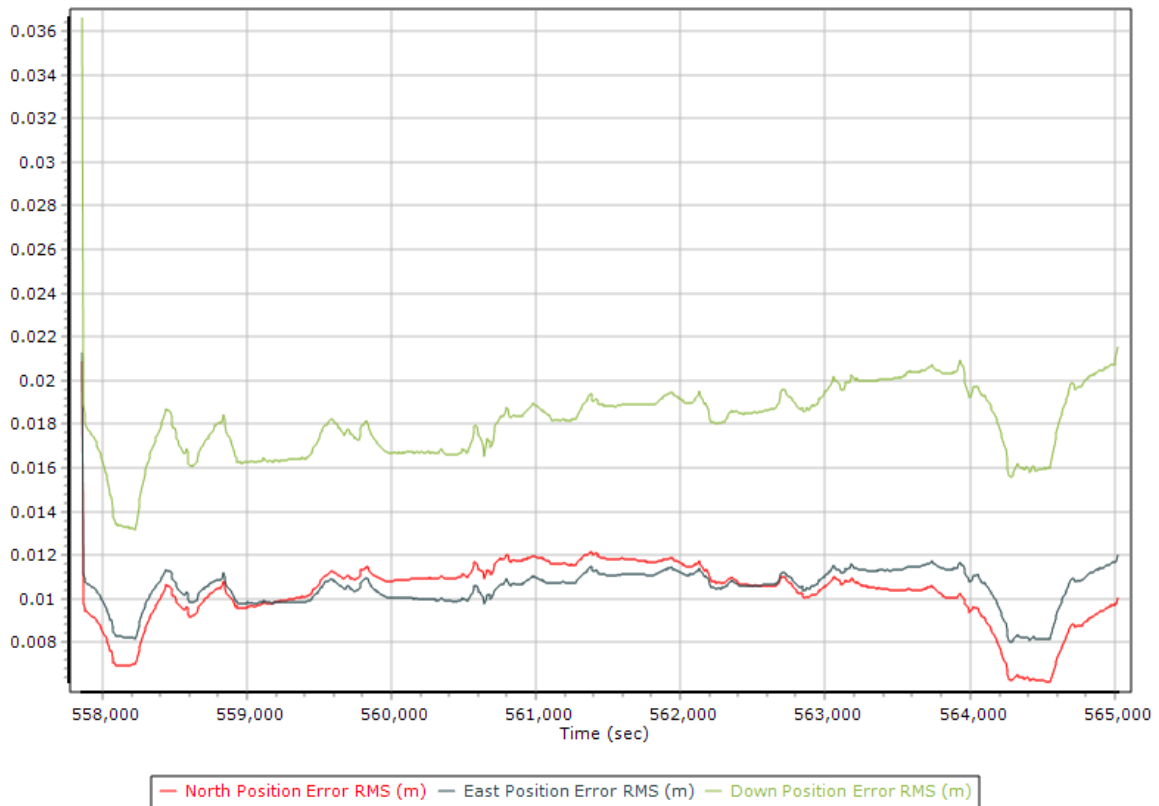
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

Timing

Start	216049.680	Data	Incr. (sec)
End	219138.000	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

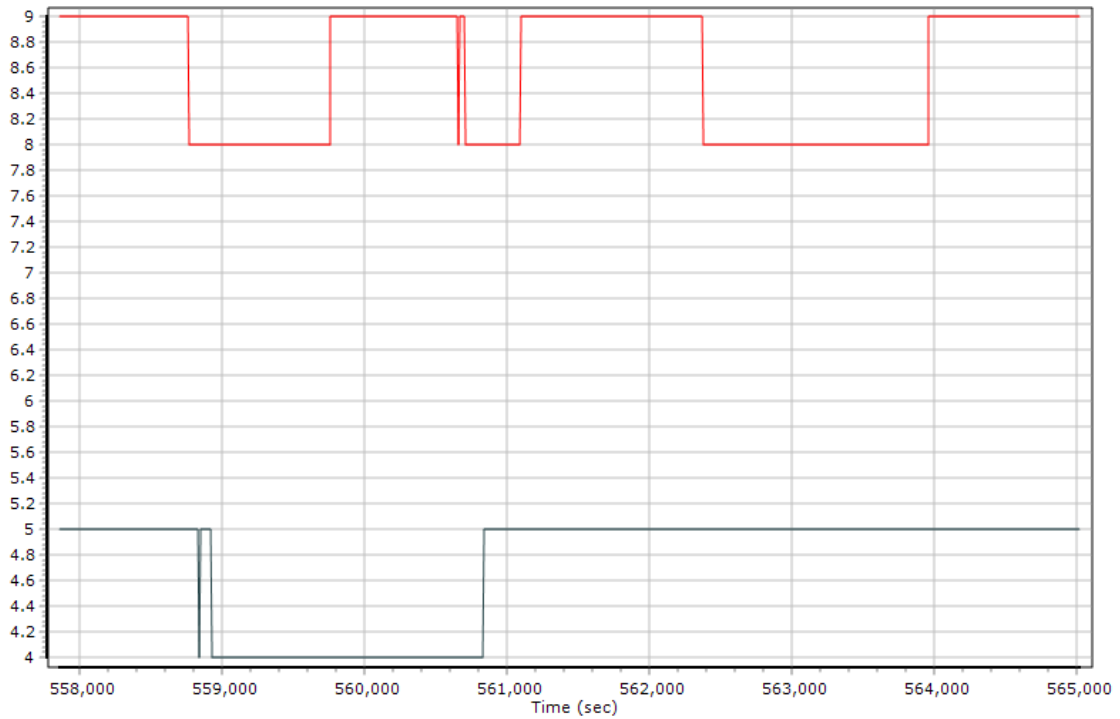
UTC Offset 18.000





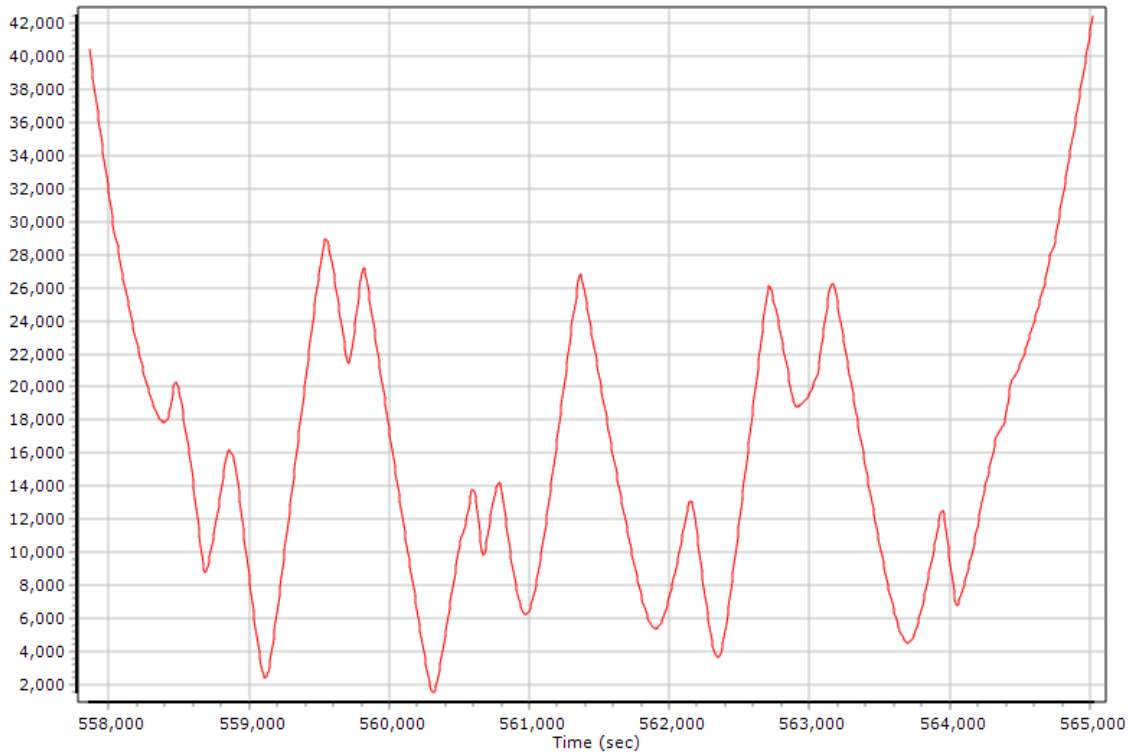


— North (m) — East (m) — Down (m) — DR mode

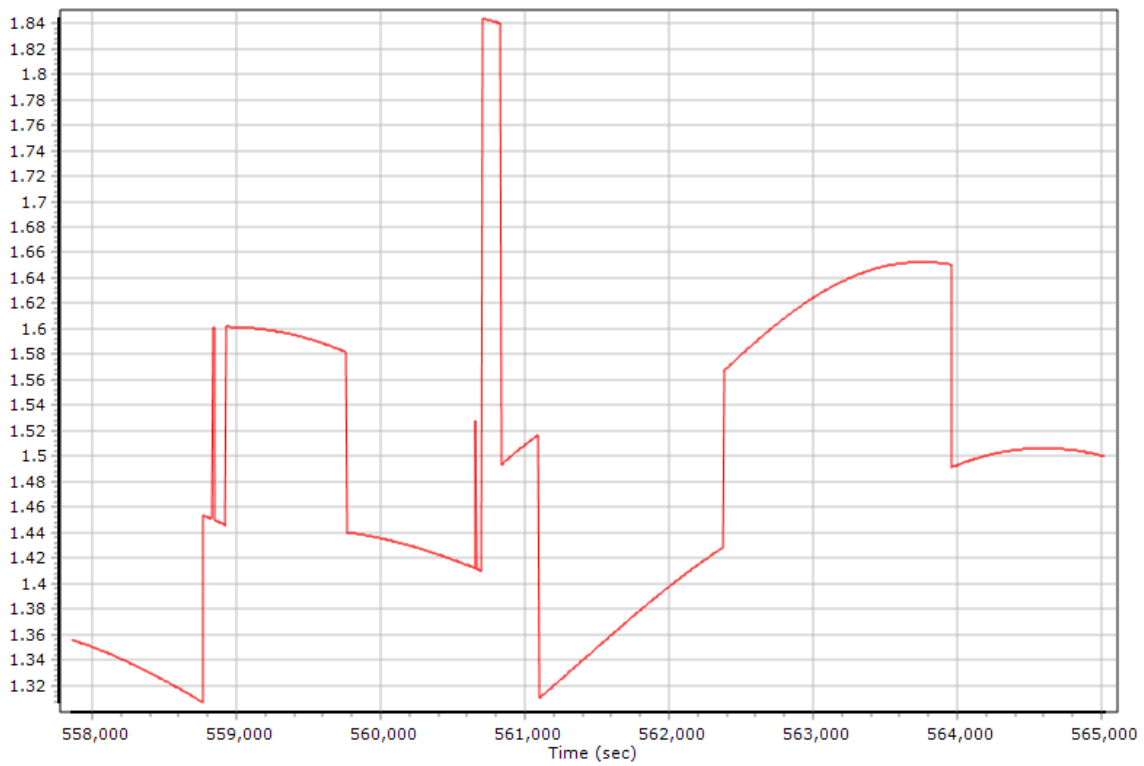


— Number of GPS Satellites — Number of GLONASS Satellites

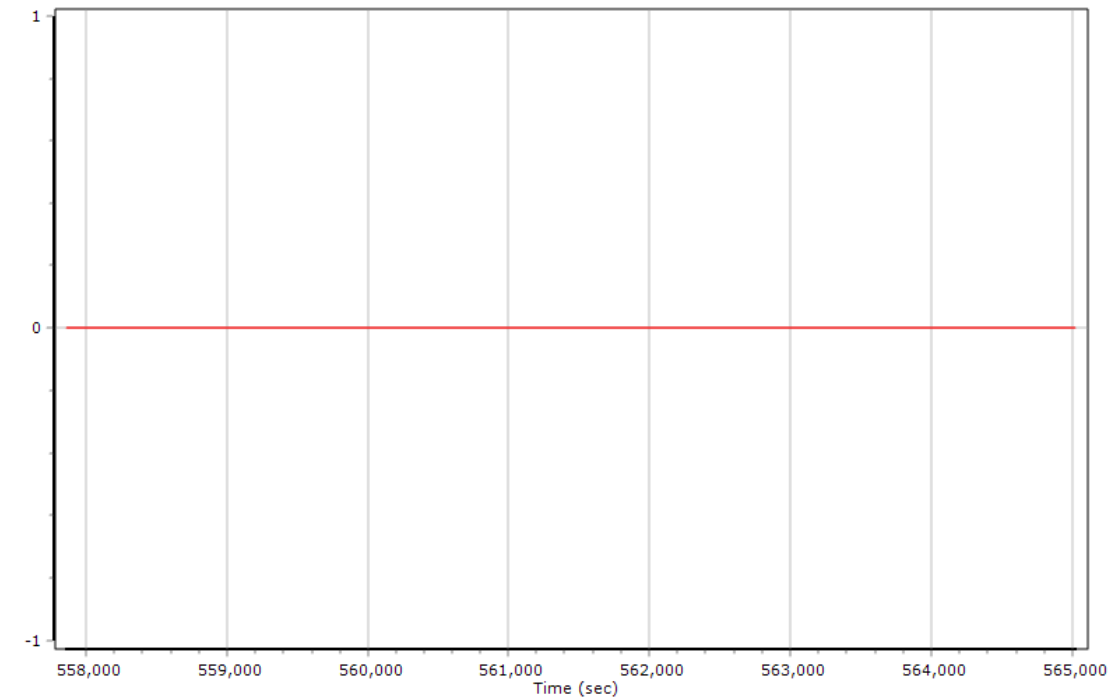
Baseline Length (m)



PDOP

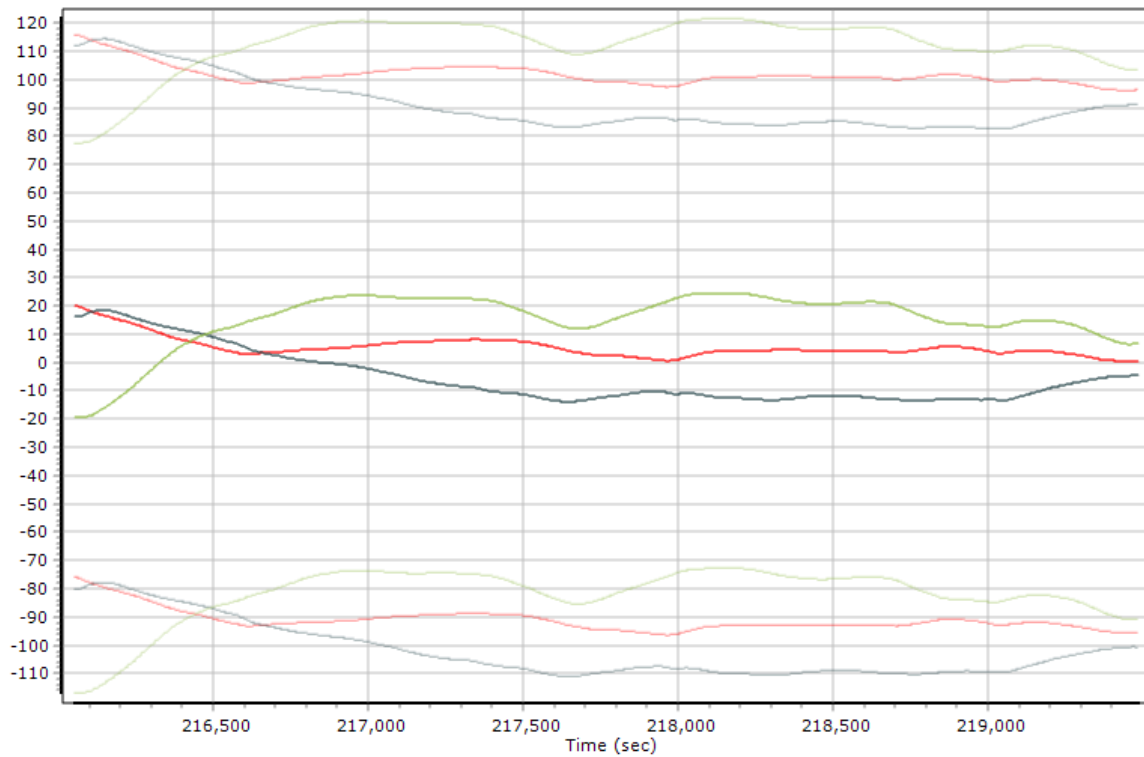


Processing mode

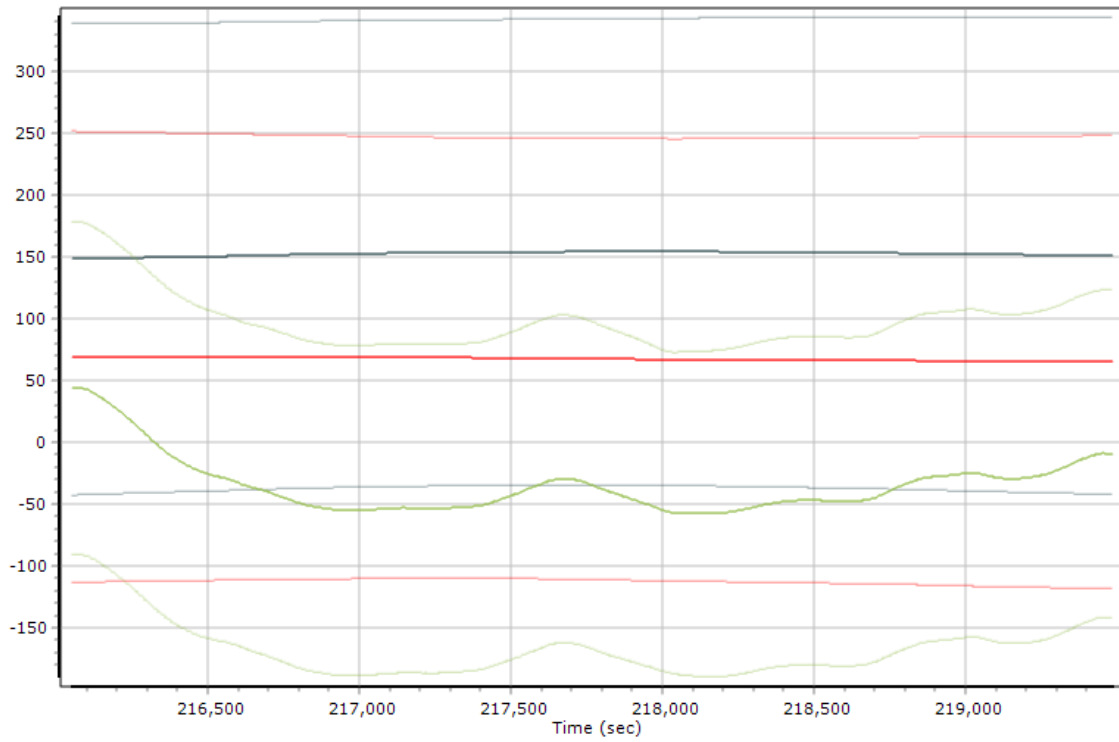


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

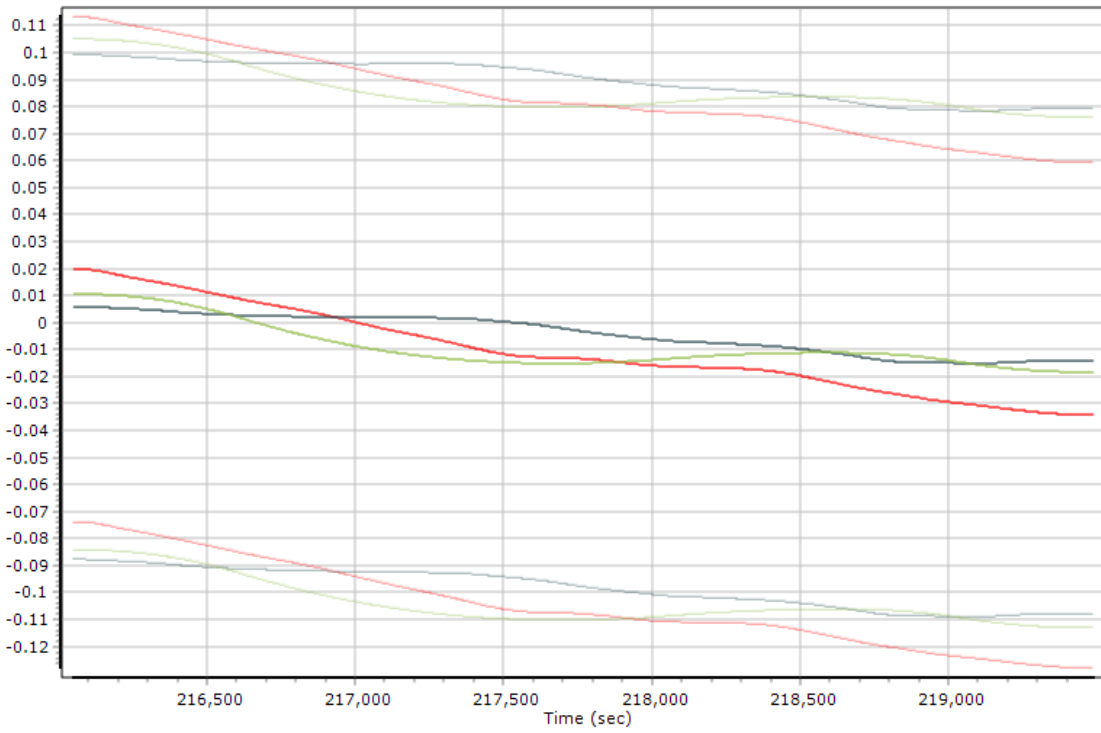
Sensor Errors



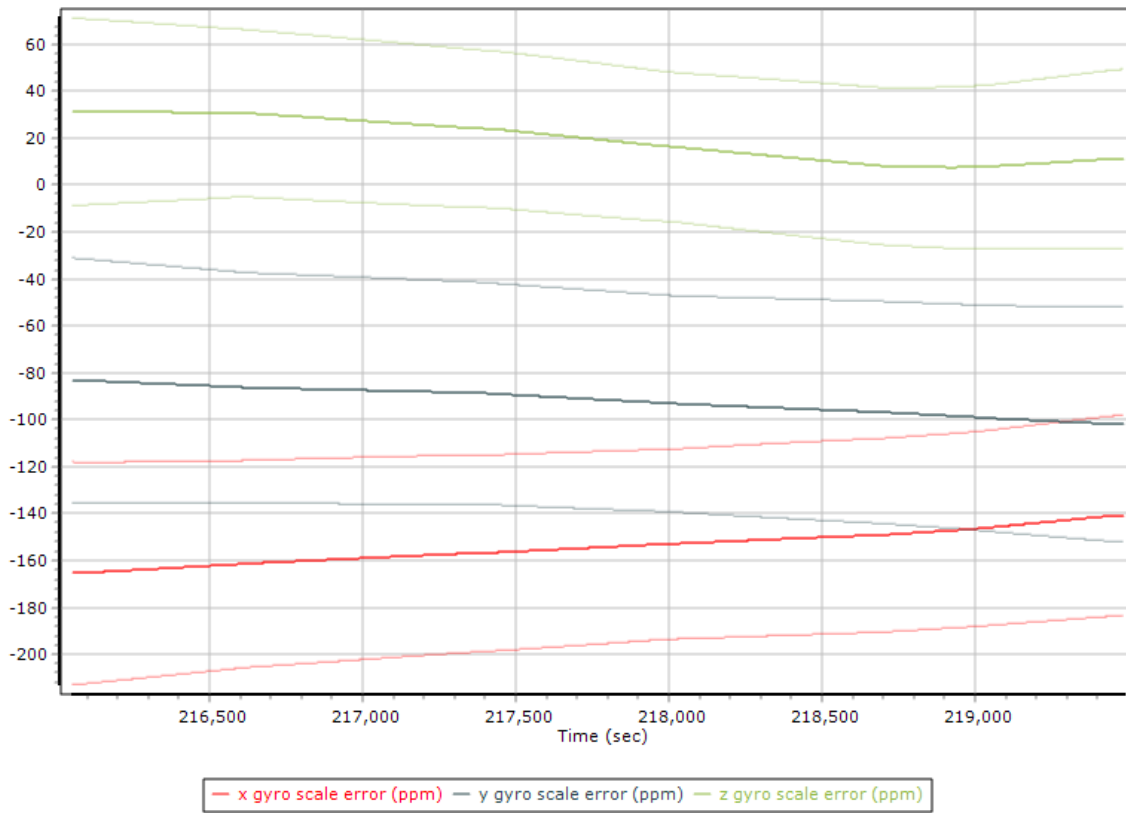
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



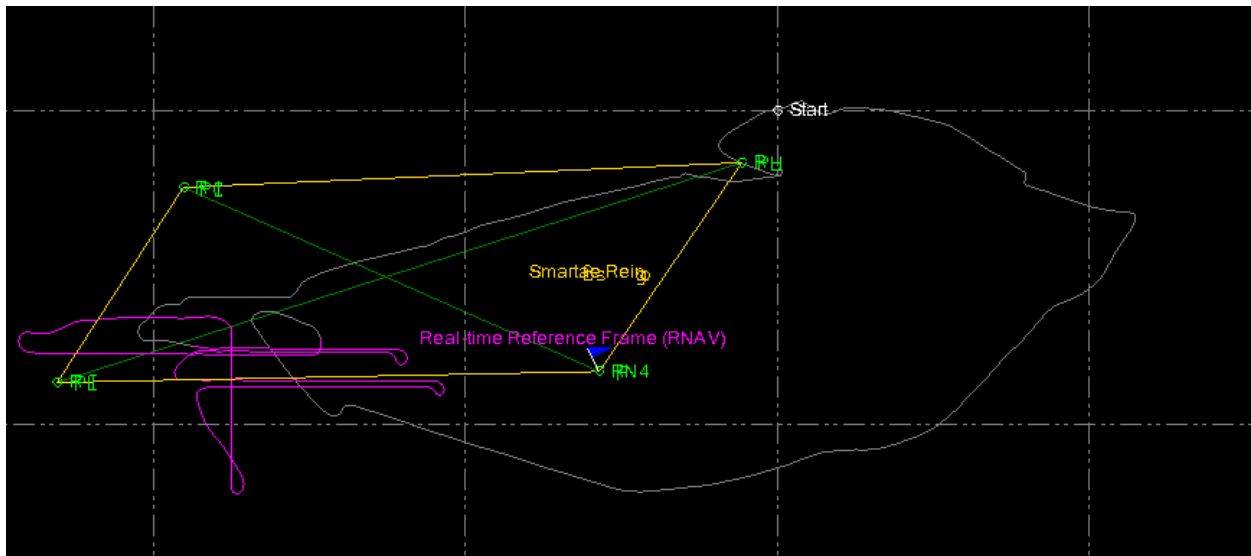
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

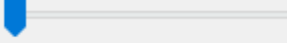


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

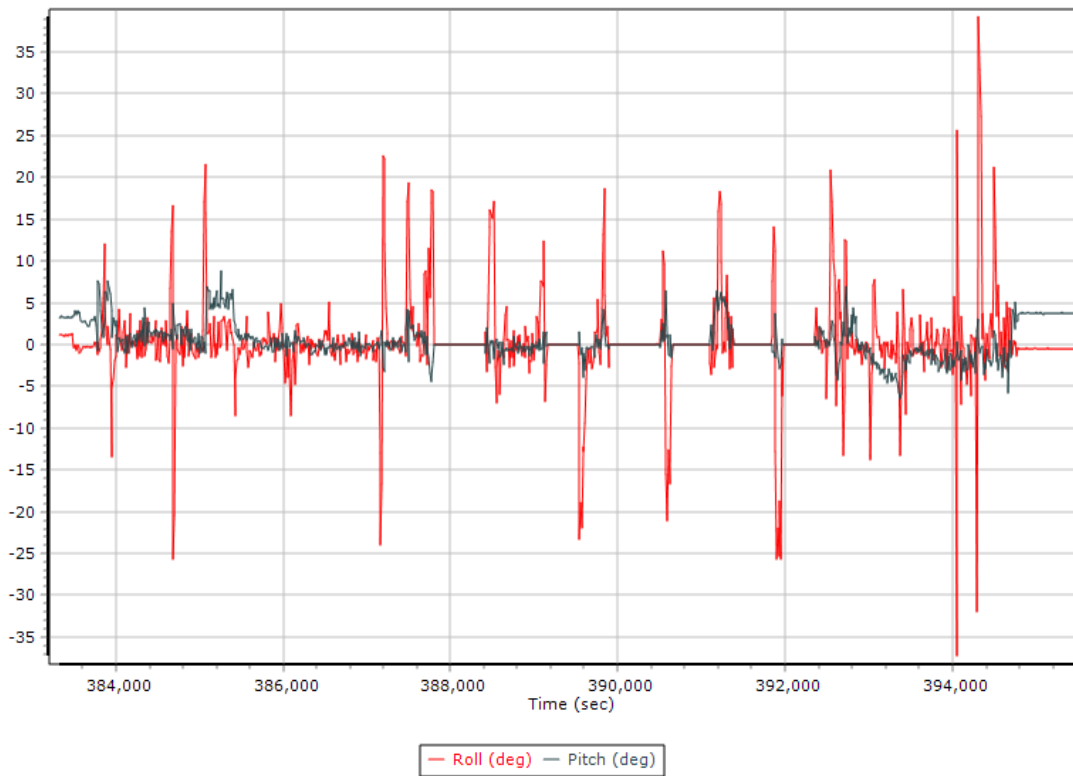
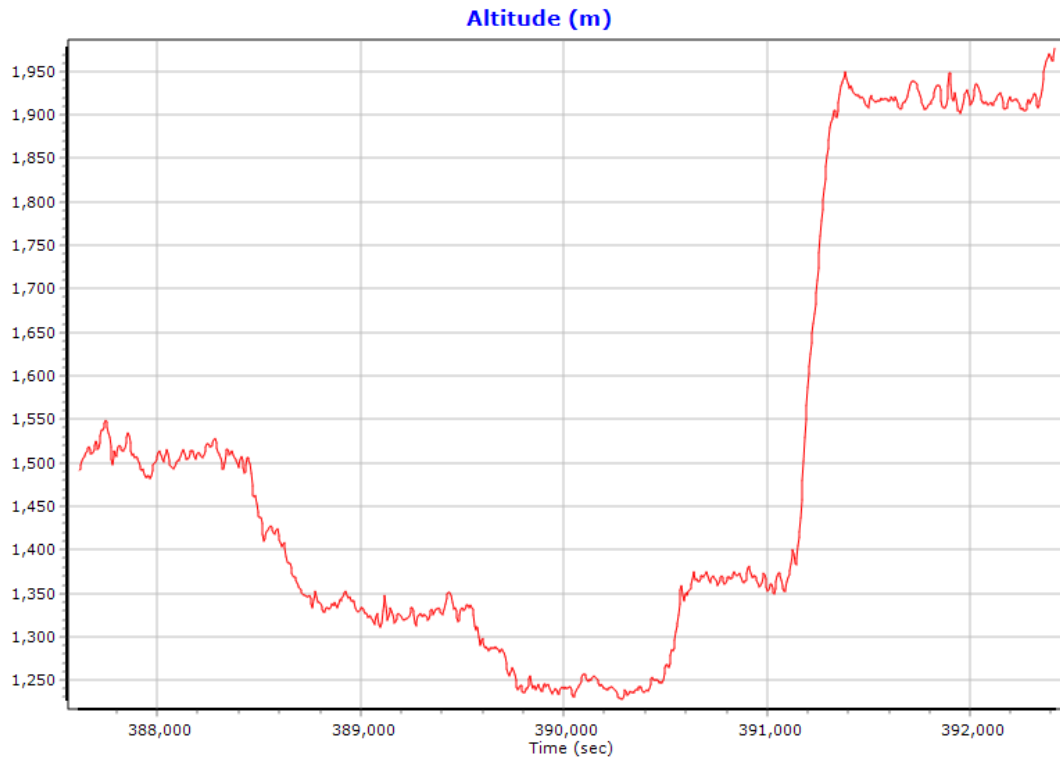


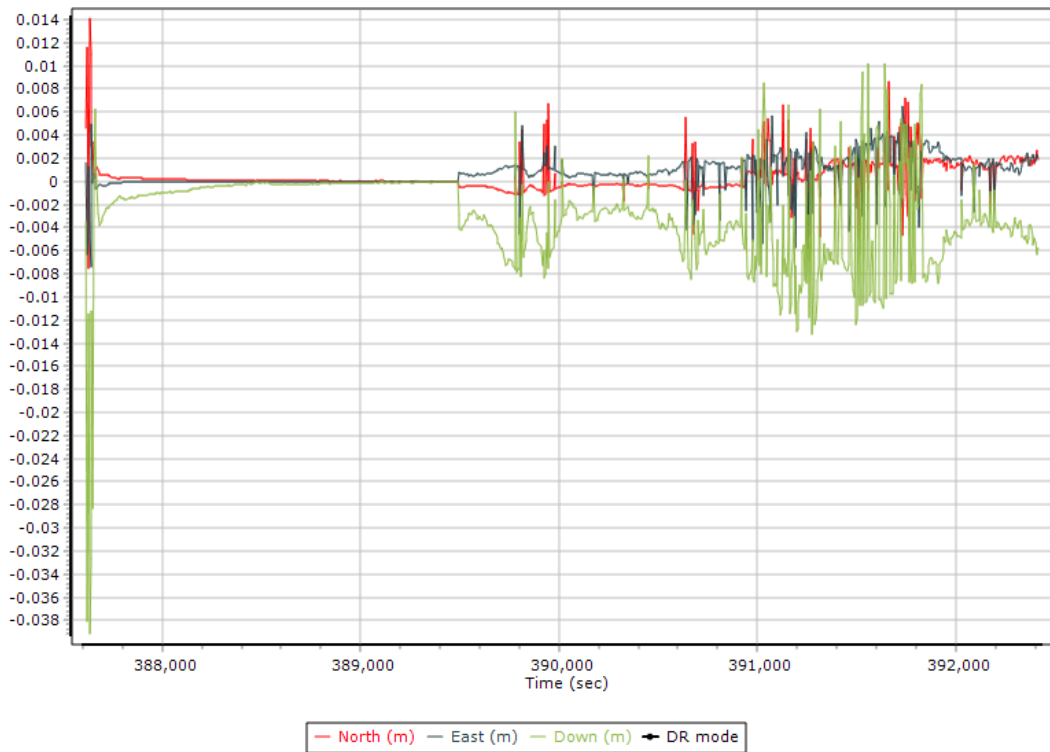
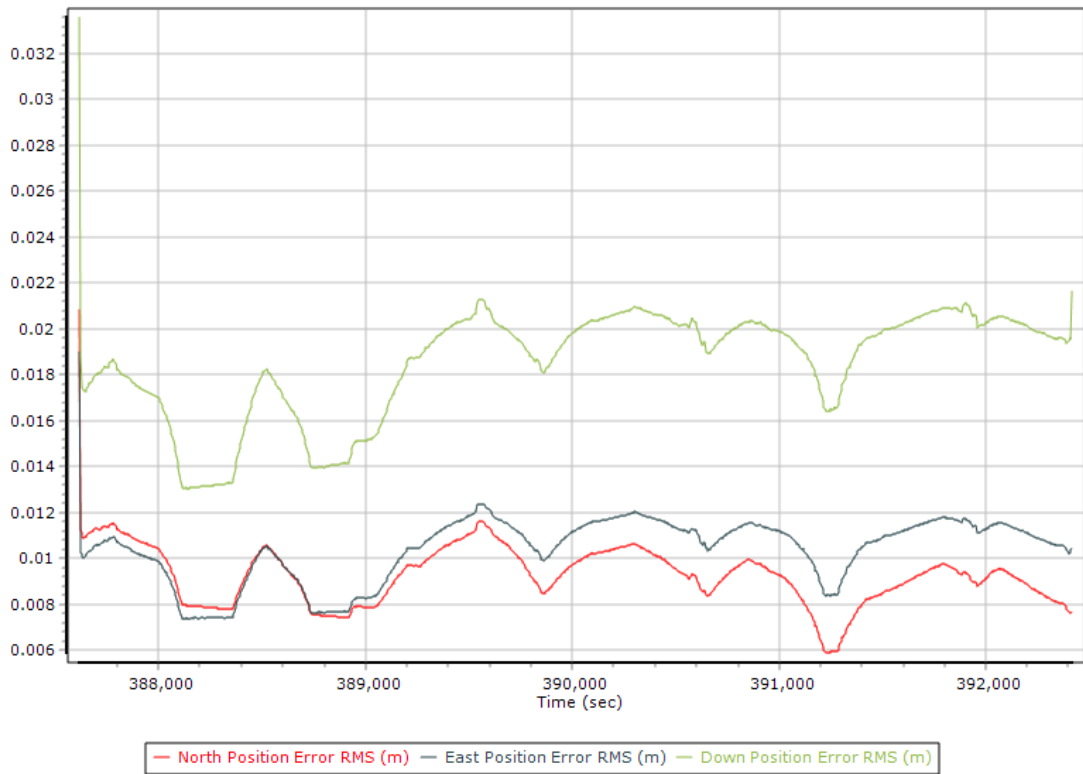
AZT18151A

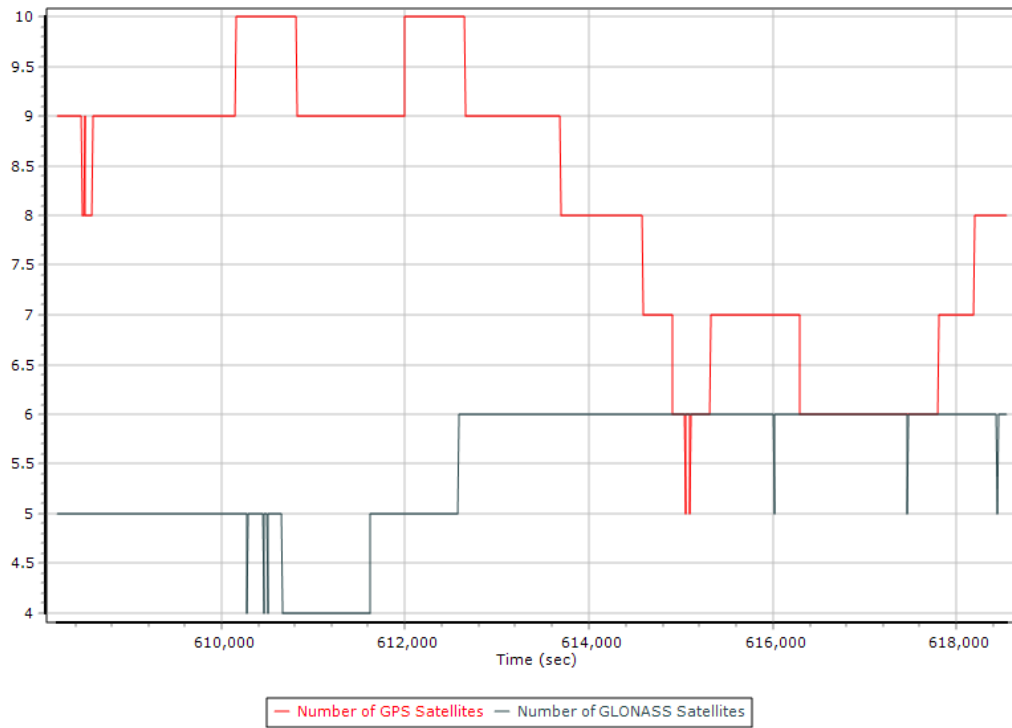


Stabilized Mount to IMU Lever Arm X: <input type="text" value="-0.034 m"/> Y: <input type="text" value="-0.010 m"/> Z: <input type="text" value="-0.352 m"/>		Stabilized Mount to IMU Mounting Angles X: <input type="text" value="0.000 deg"/> Y: <input type="text" value="0.000 deg"/> Z: <input type="text"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

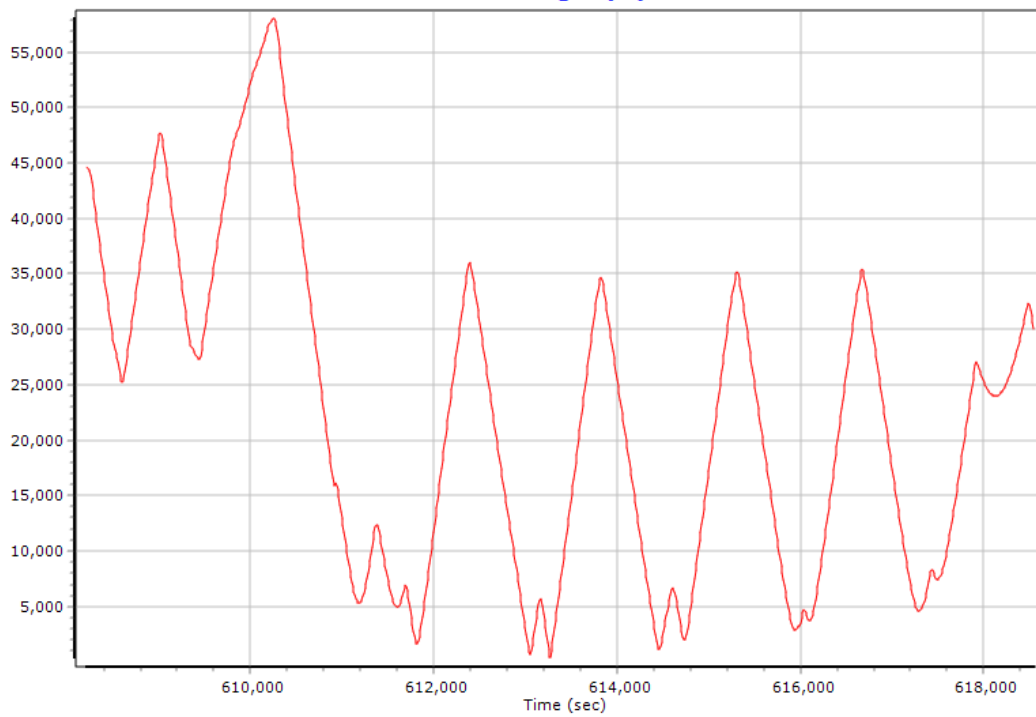
Timing Start: <input type="text" value="387734.988"/> End: <input type="text" value="392422.079"/> <input type="checkbox"/> Entire time interval <input checked="" type="checkbox"/> Seconds of start week UTC Offset: <input type="text" value="18.000"/>		<table border="1"> <thead> <tr> <th>Data</th> <th>Incr. (sec)</th> </tr> </thead> <tbody> <tr> <td>Output Record</td> <td>0.005000</td> </tr> <tr> <td>IMU</td> <td>0.005000</td> </tr> <tr> <td>Primary GNSS</td> <td>1.000000</td> </tr> </tbody> </table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000
Data	Incr. (sec)									
Output Record	0.005000									
IMU	0.005000									
Primary GNSS	1.000000									

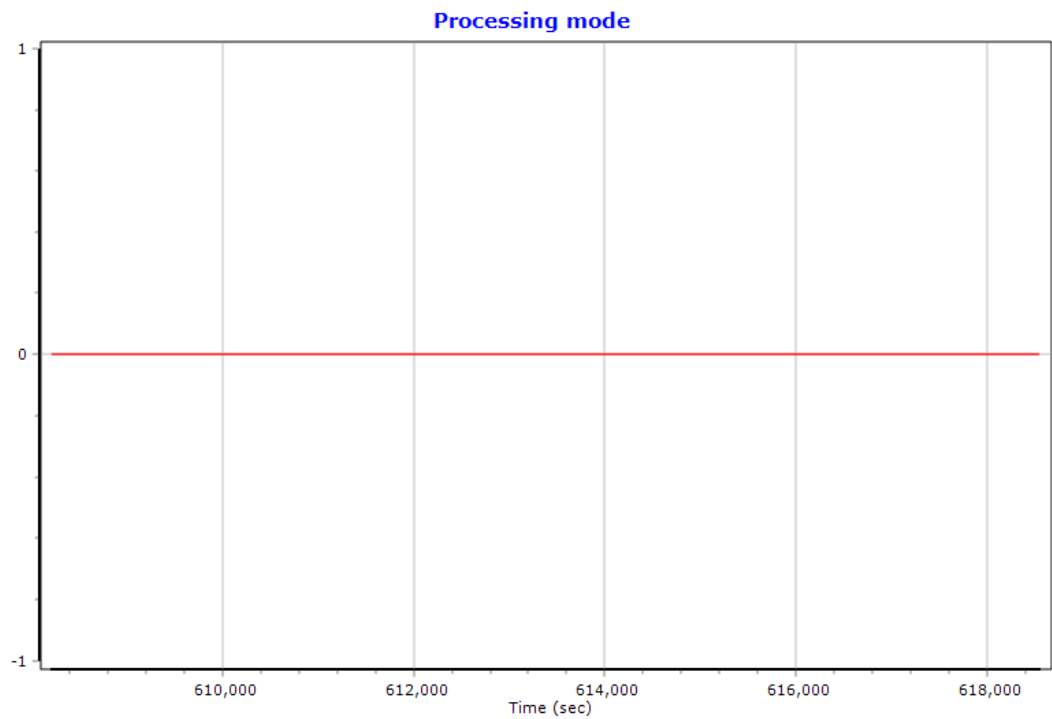
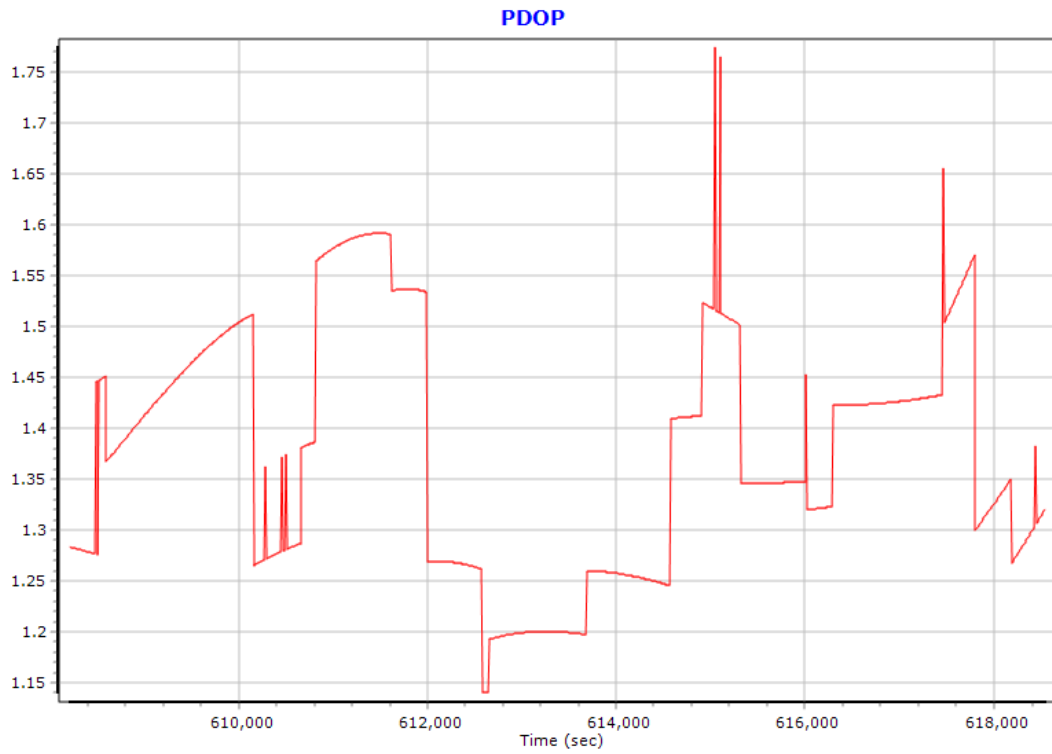






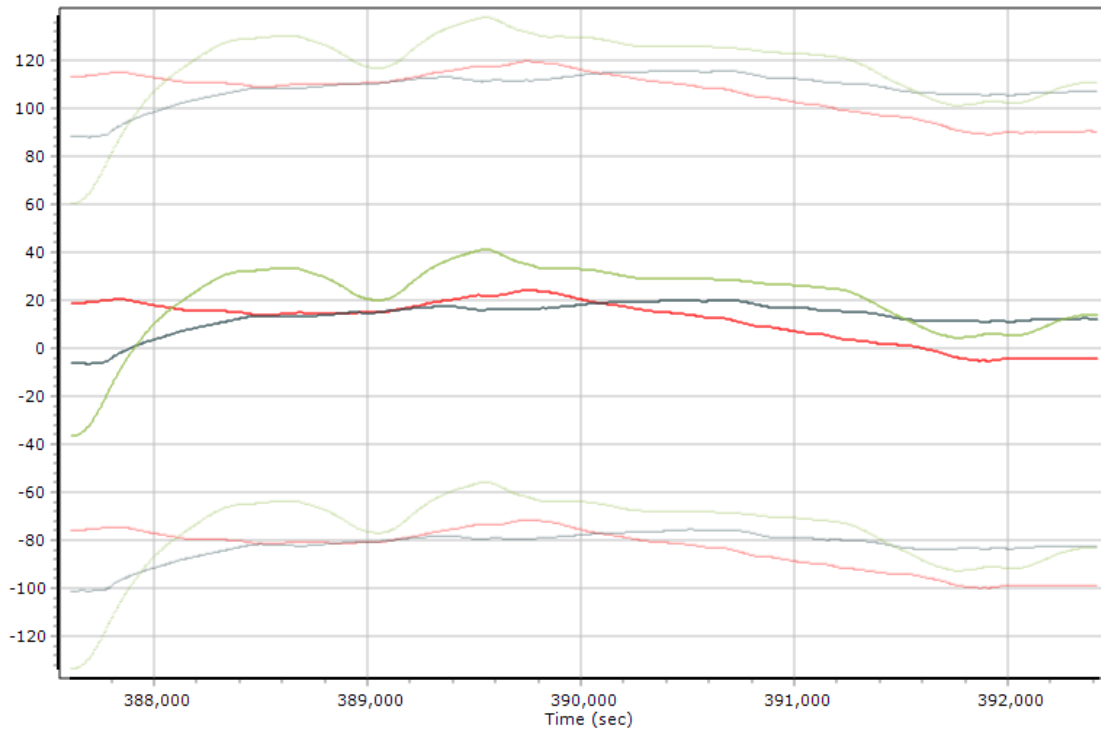
Baseline Length (m)



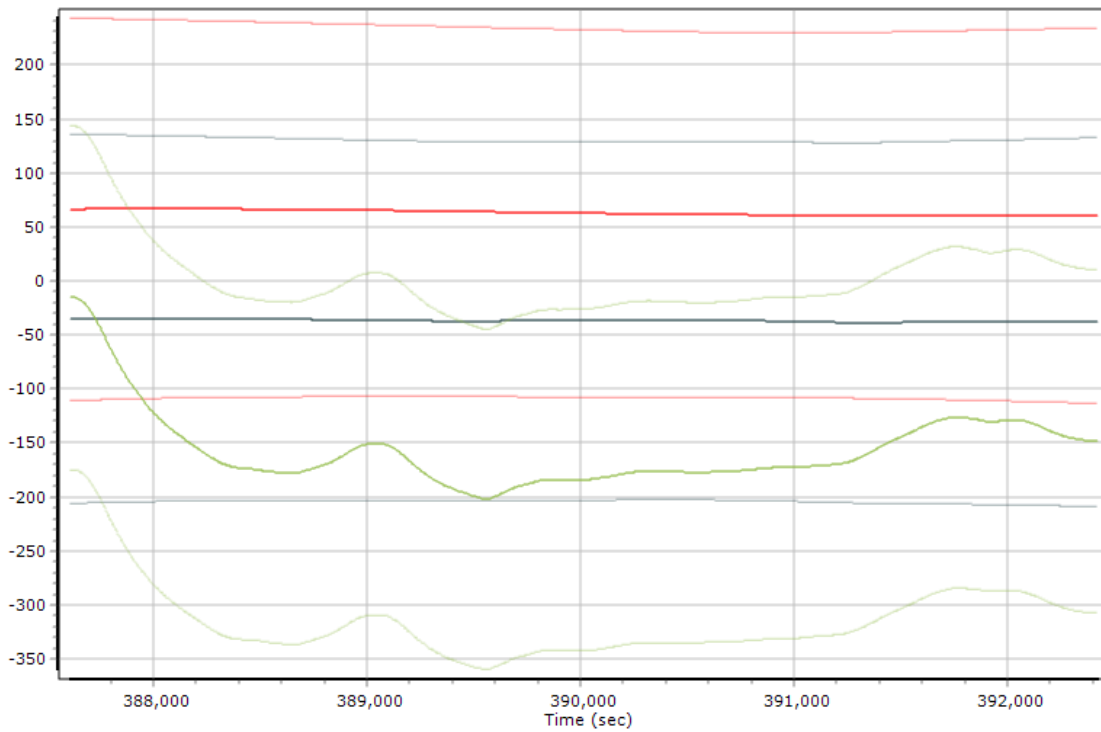


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

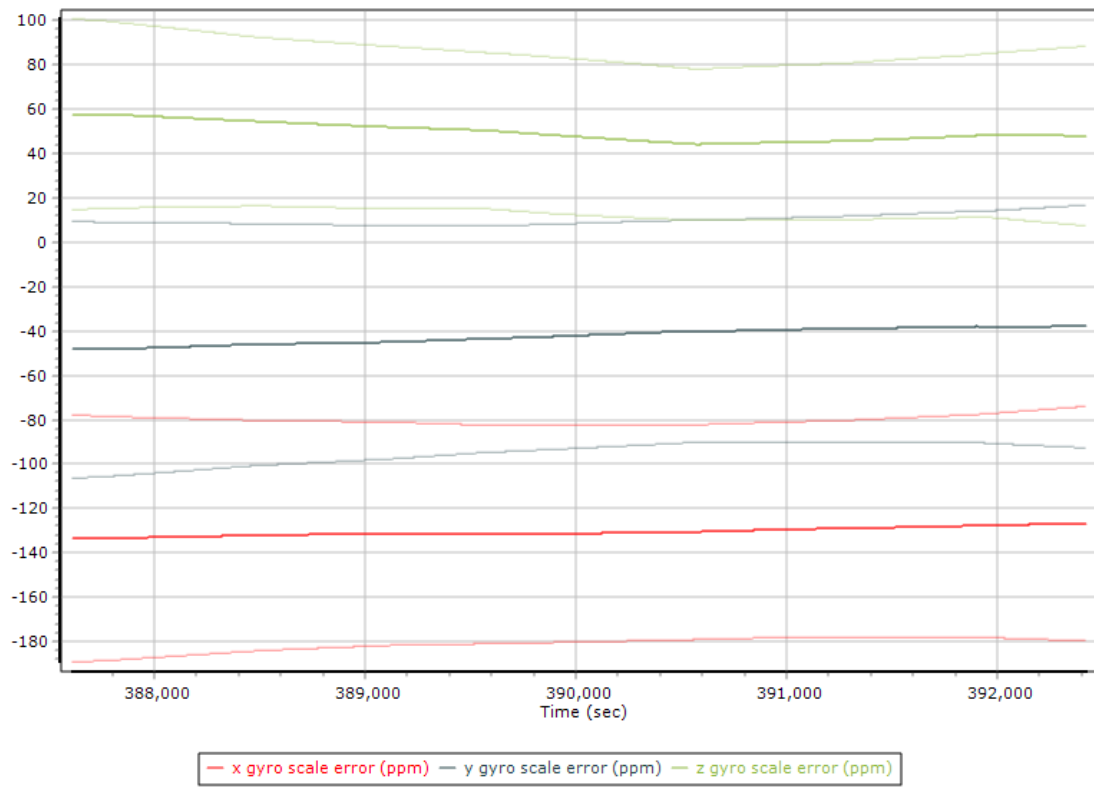
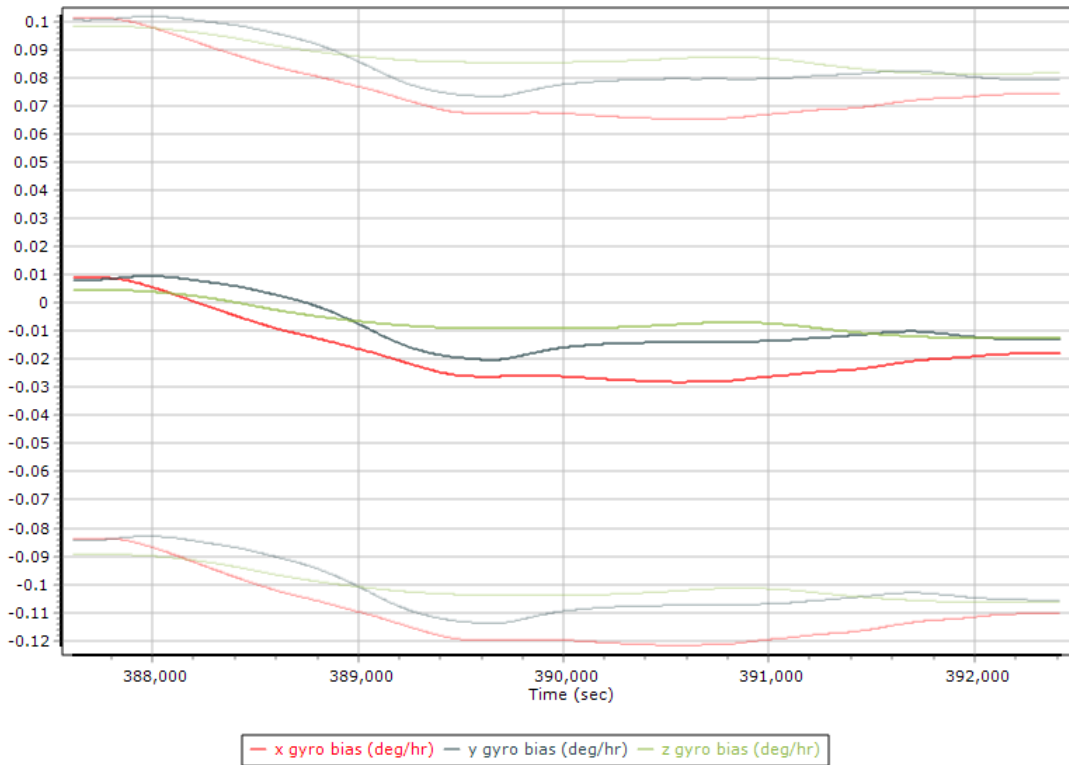
Sensor Errors



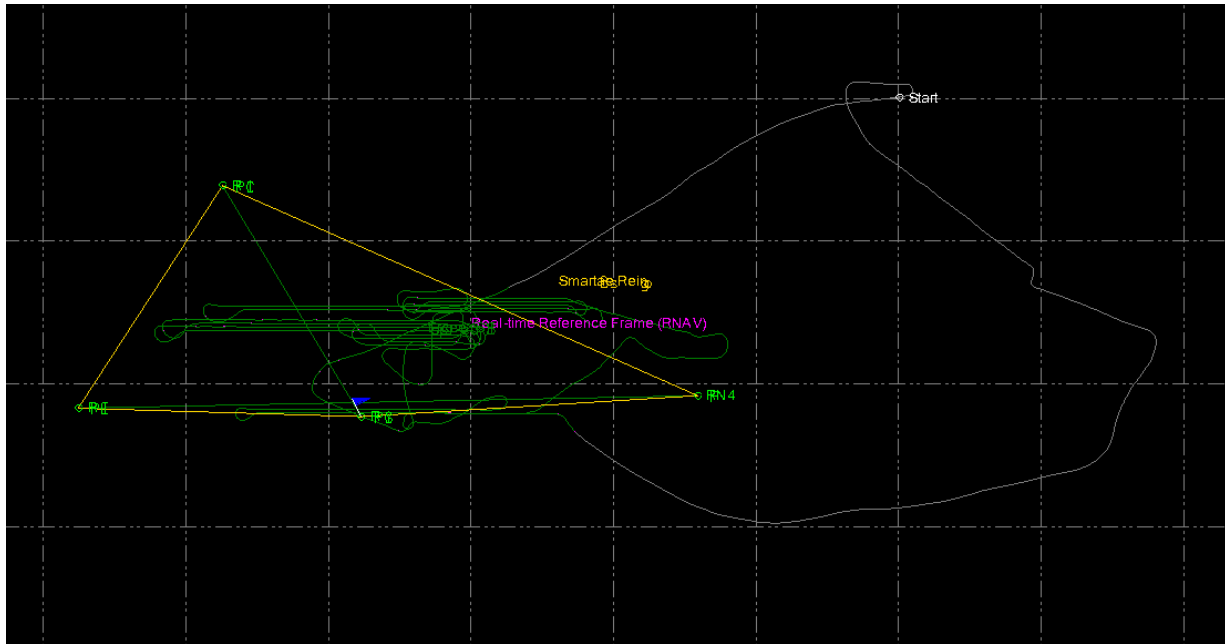
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



AZT18156A



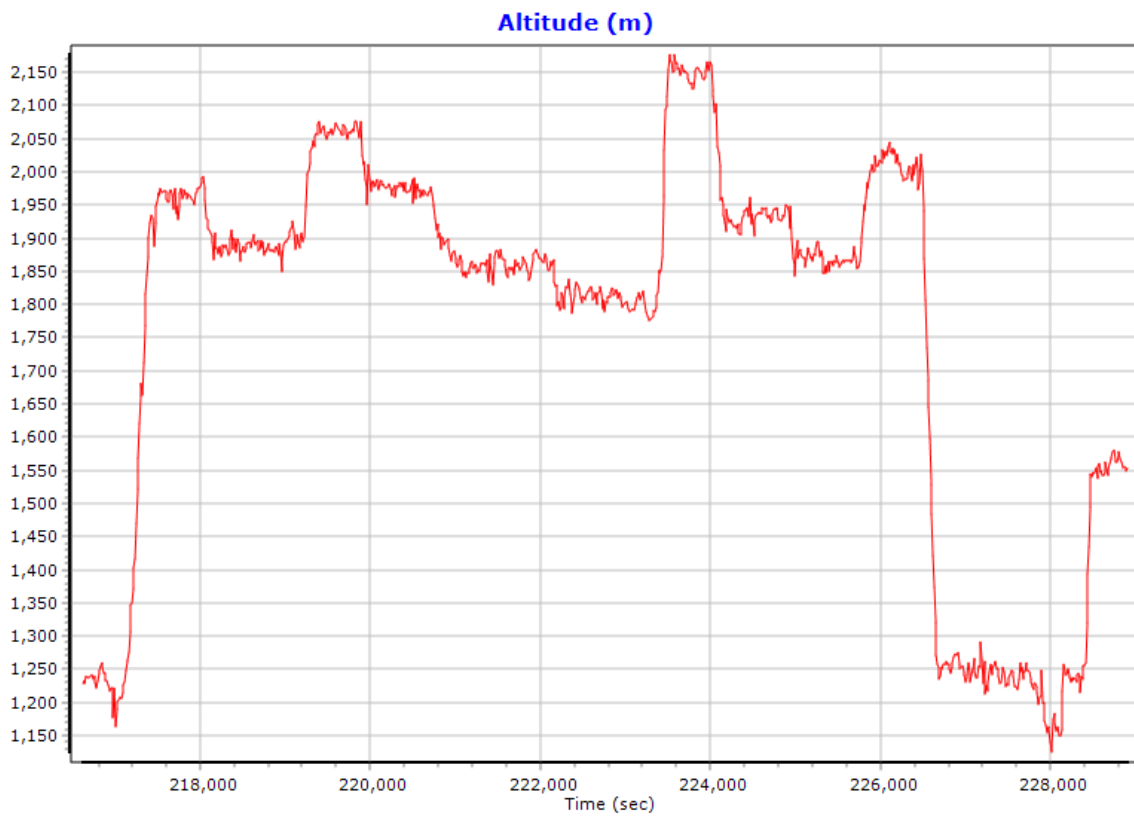
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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			

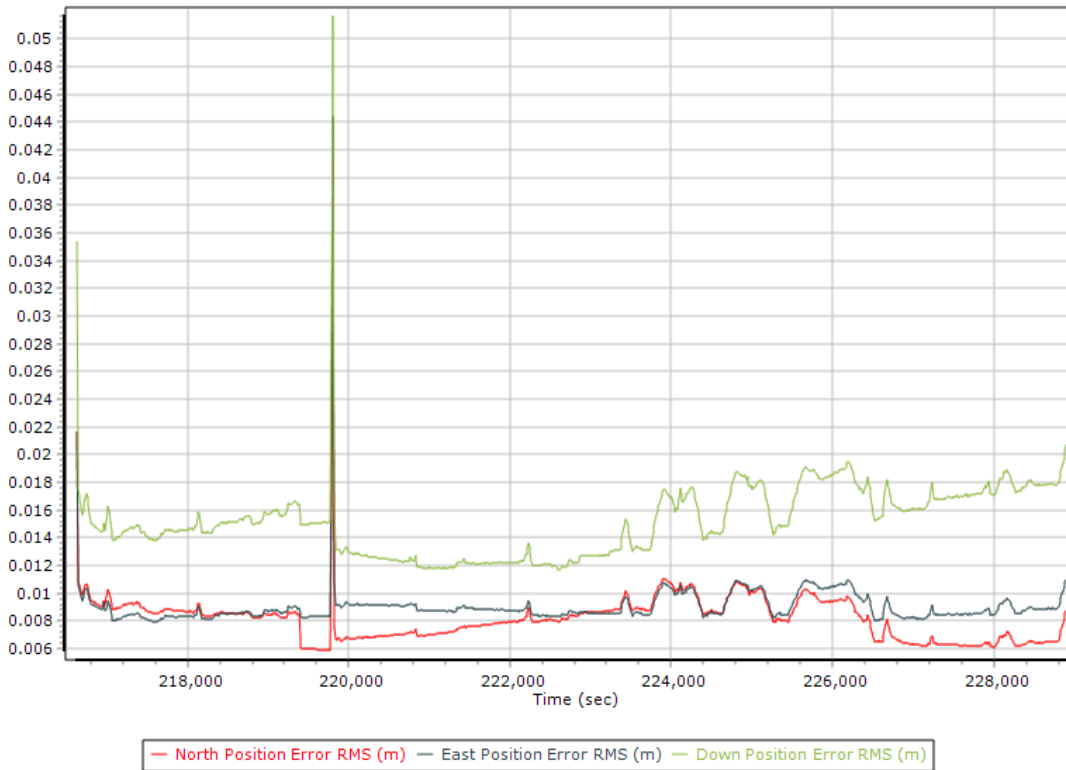
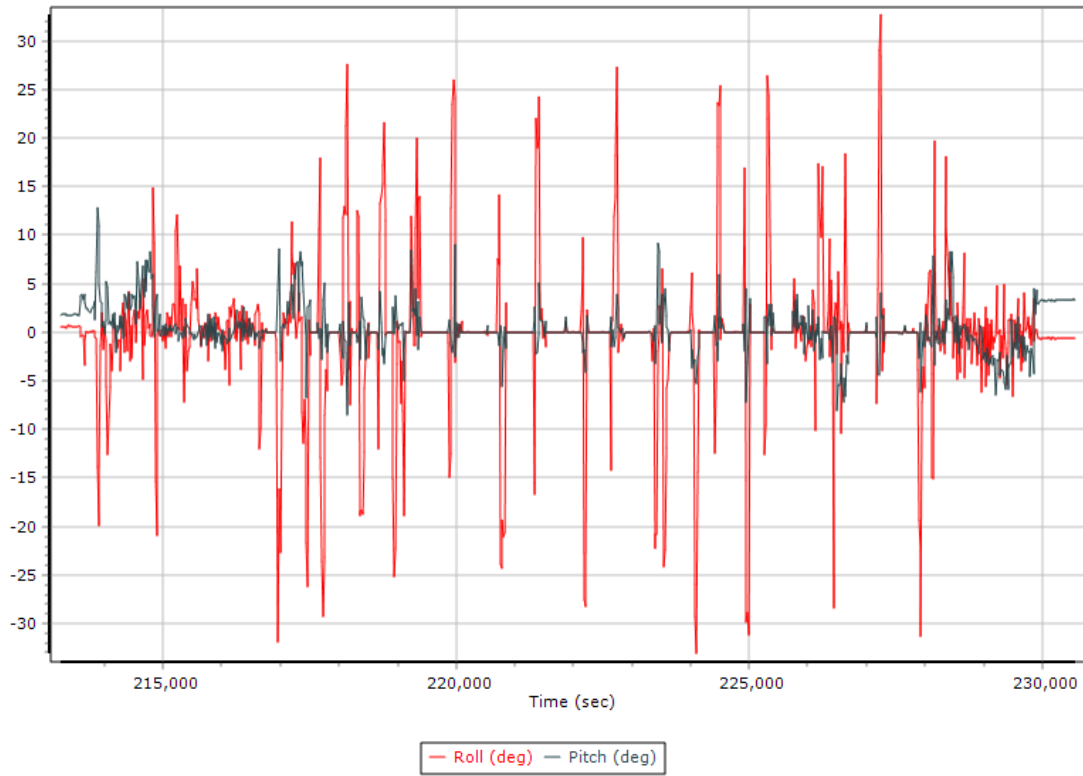
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

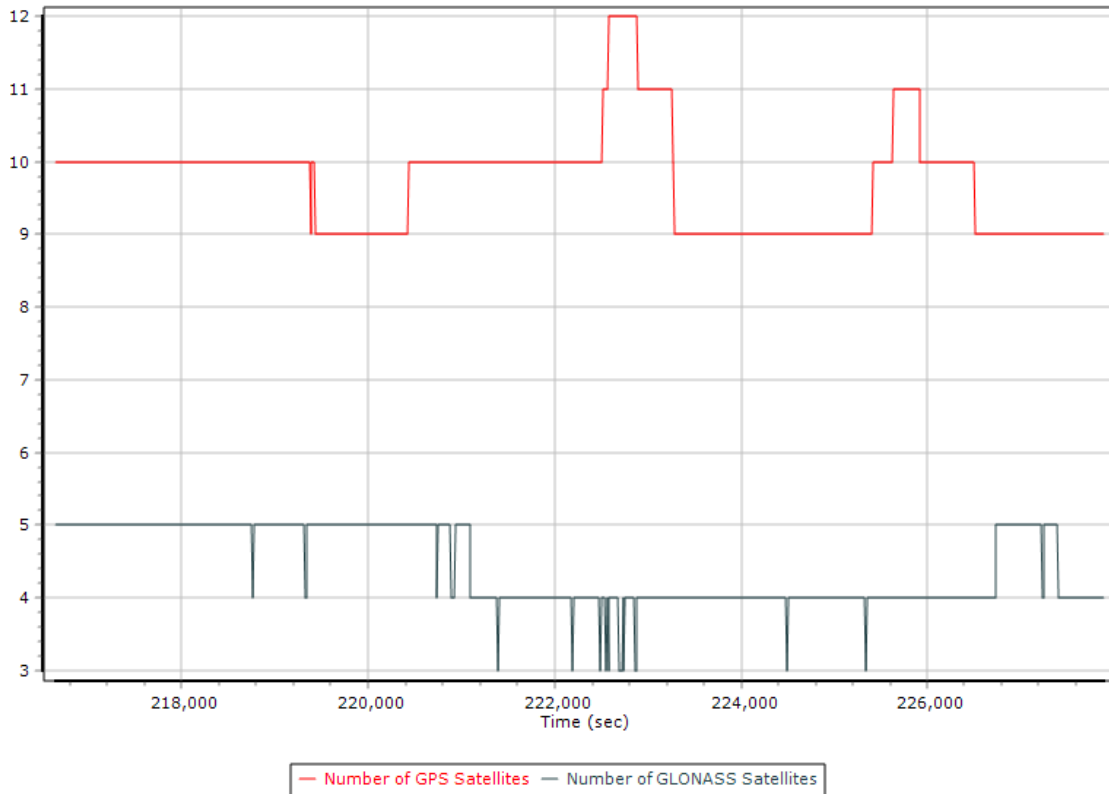
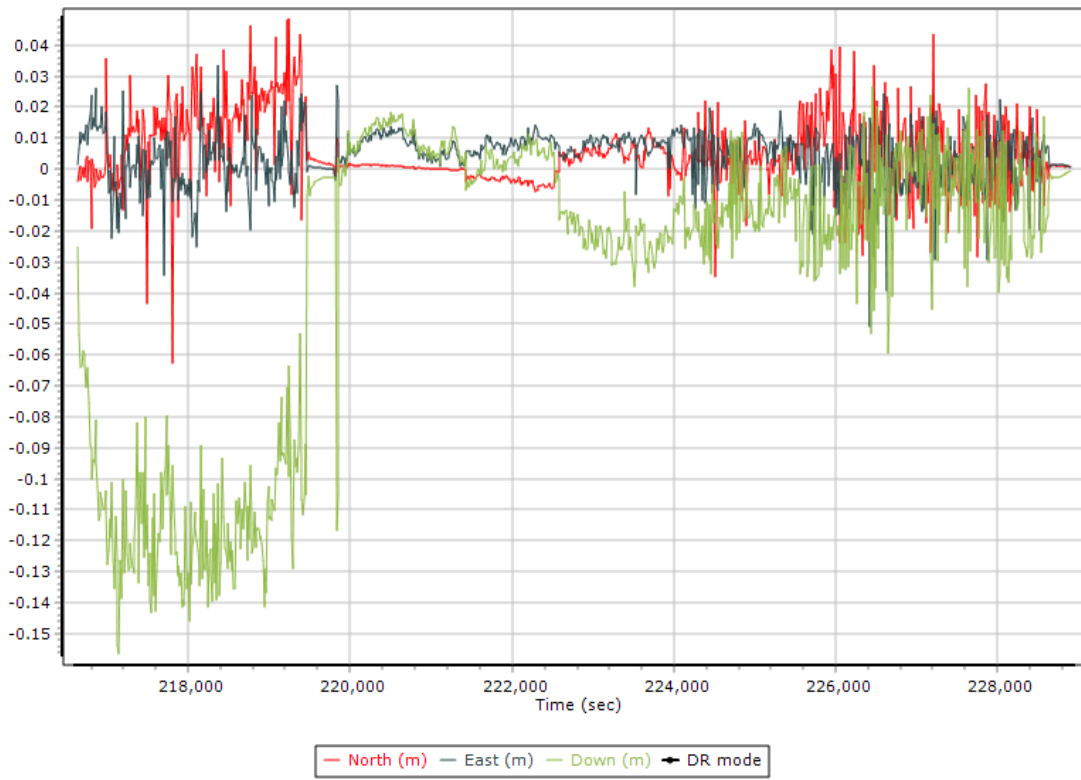
Timing

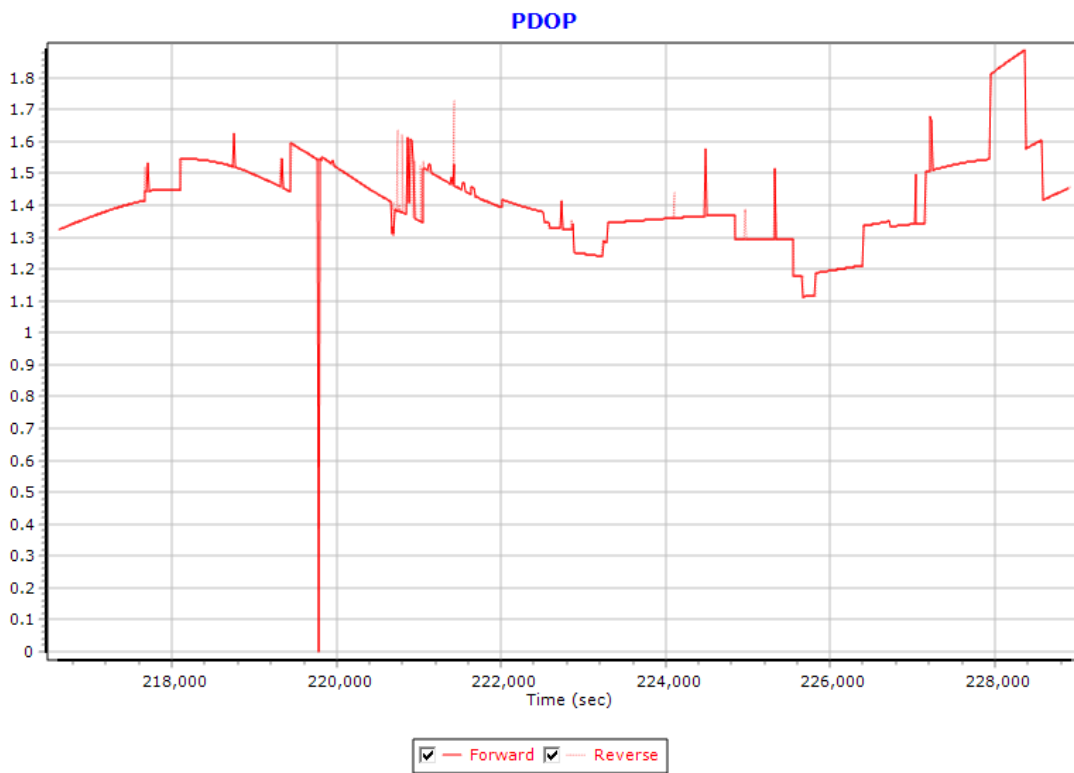
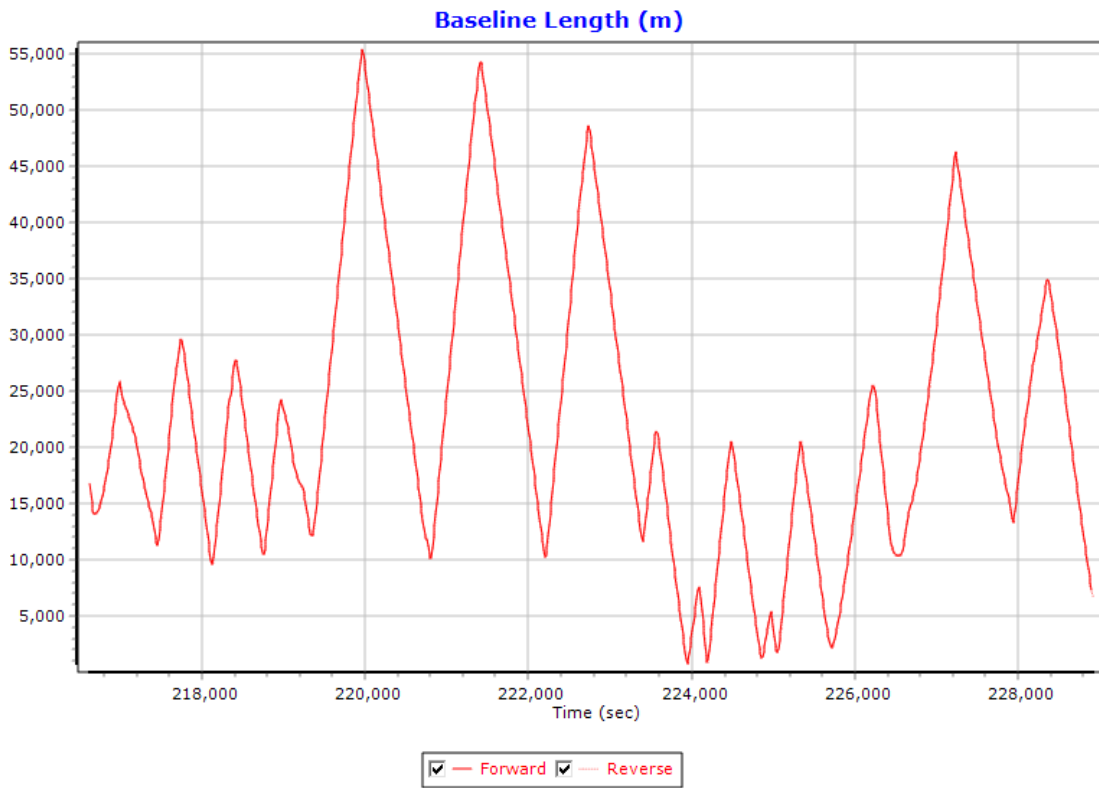
Start	<input type="text" value="216643.377"/>	Data	Incr. (sec)
End	<input type="text" value="227897.002"/>	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset

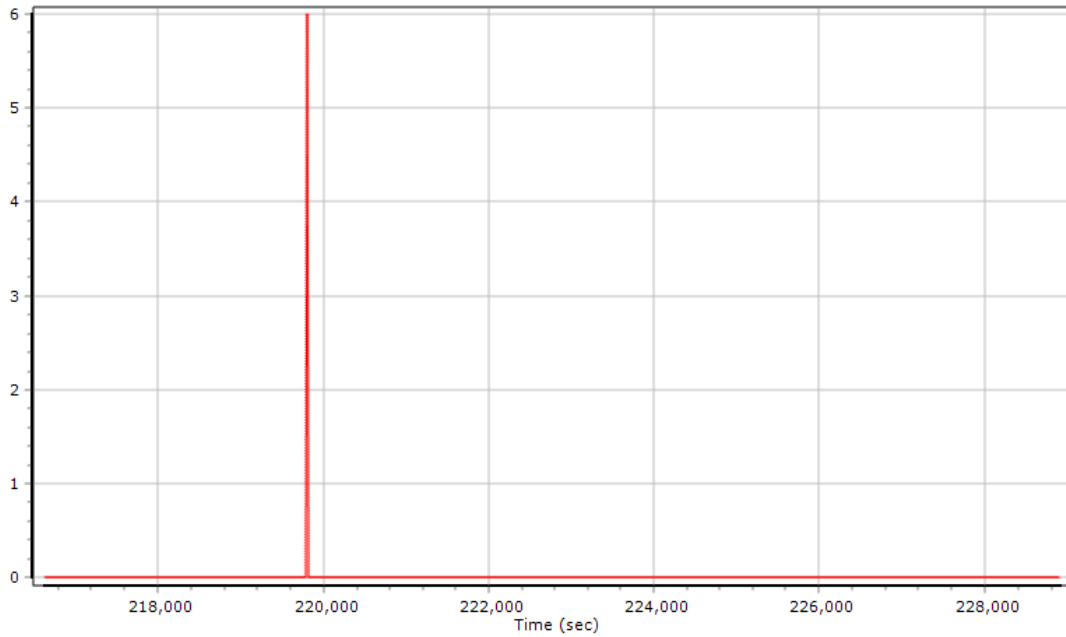








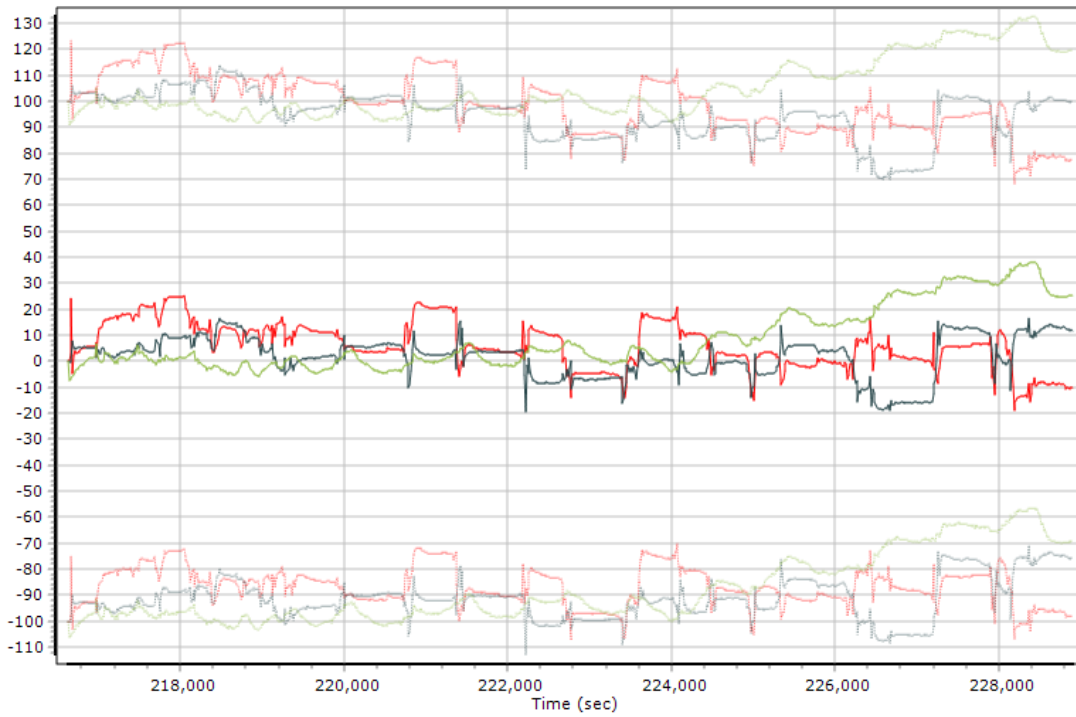
Processing mode



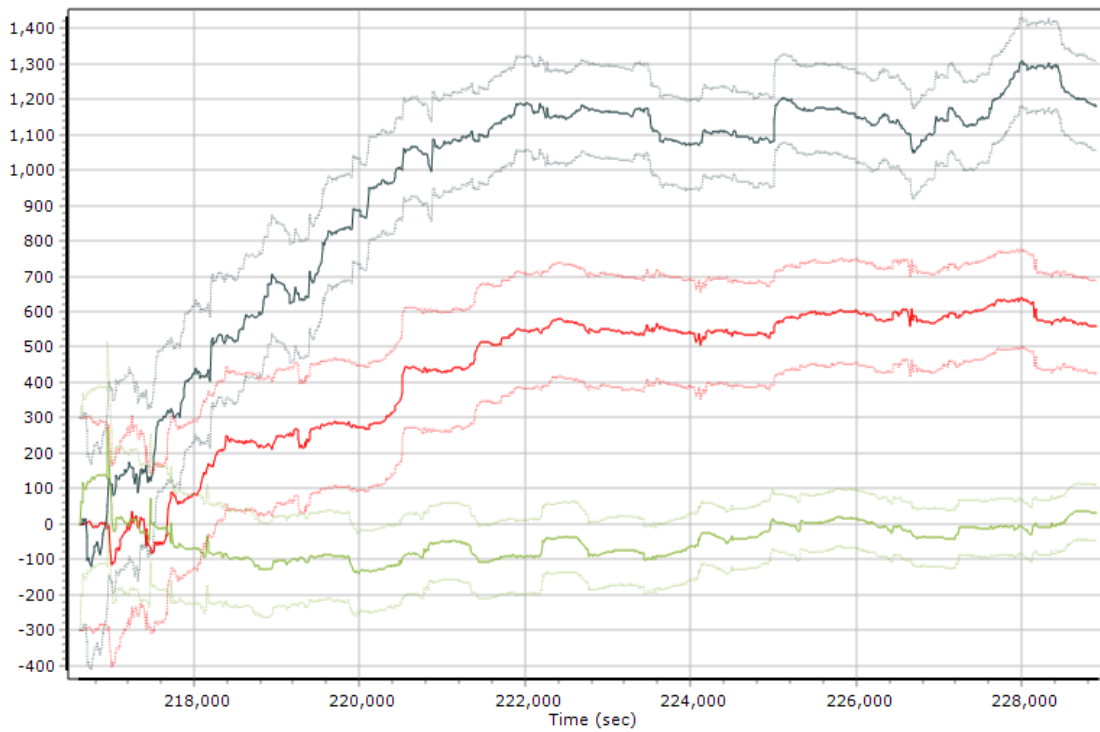
Forward Reverse

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

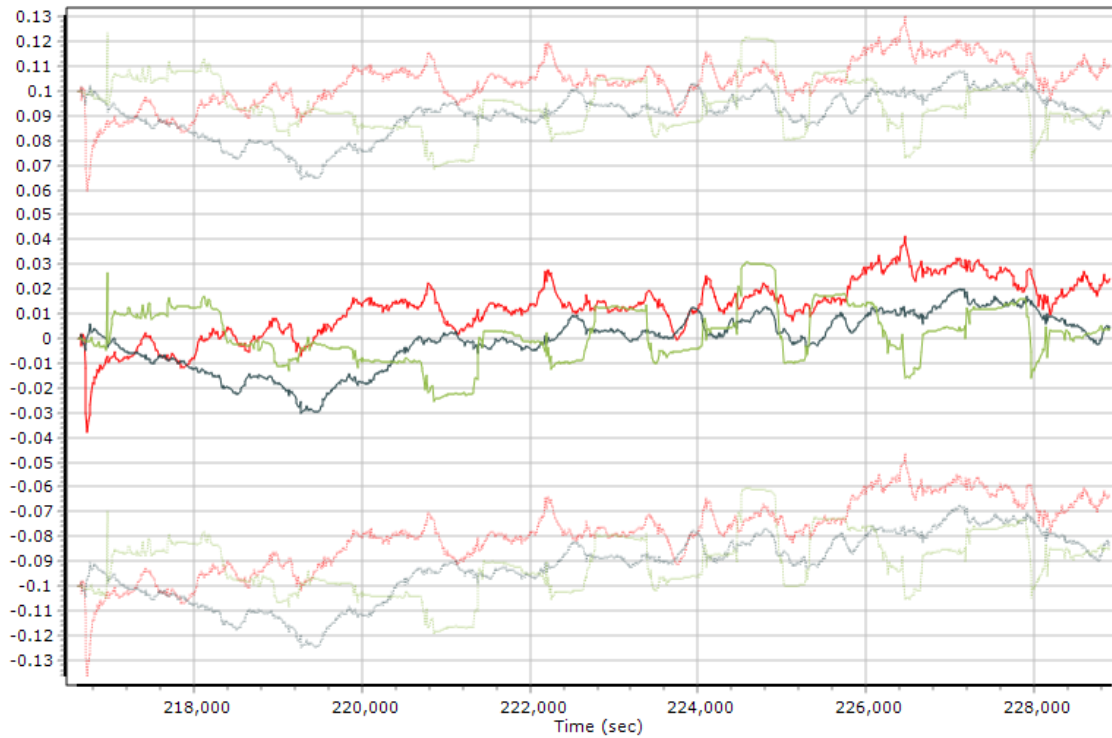
Sensor Errors



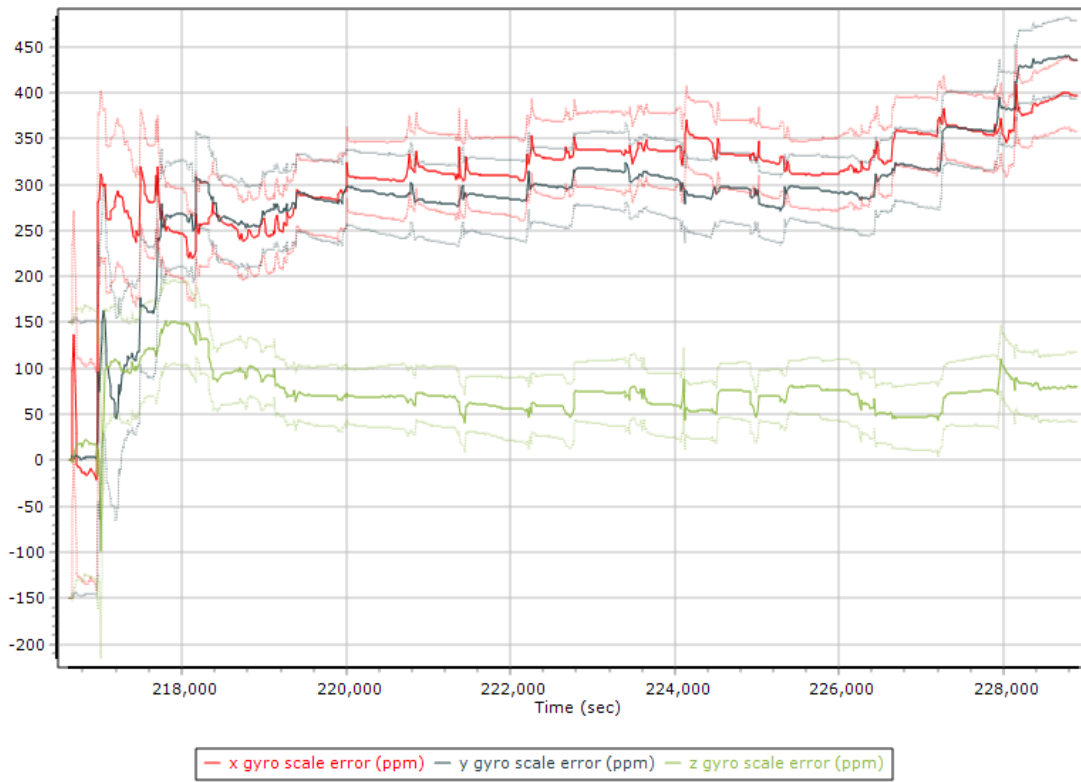
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



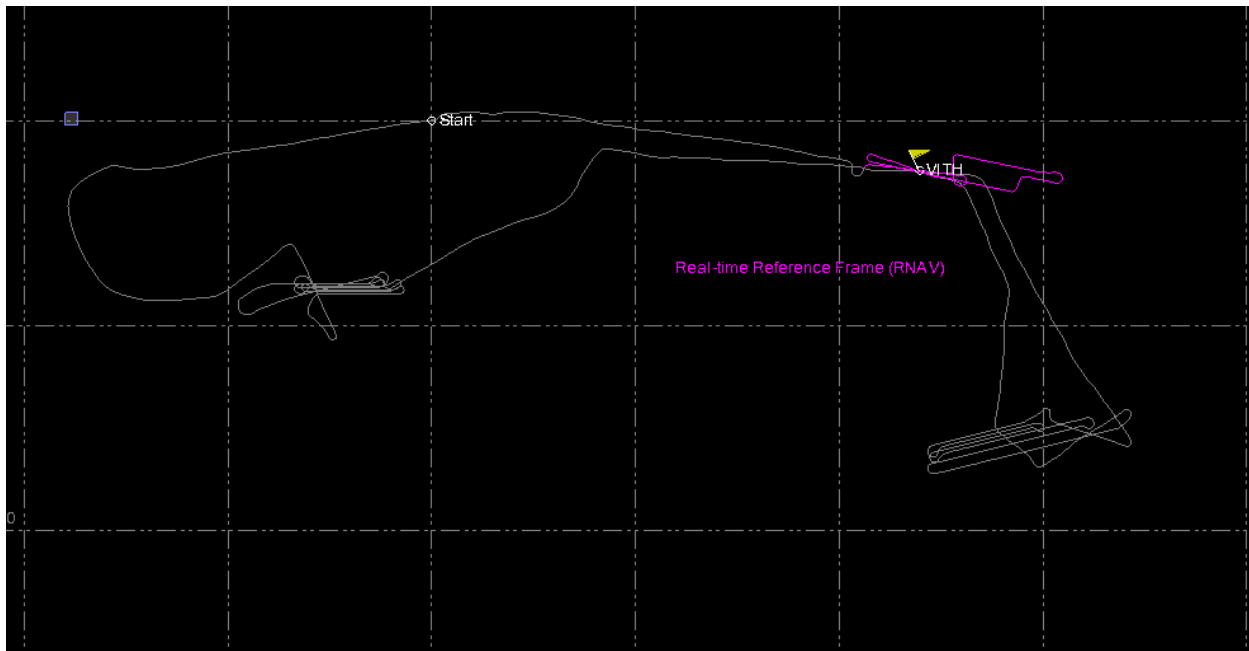
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

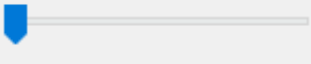


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

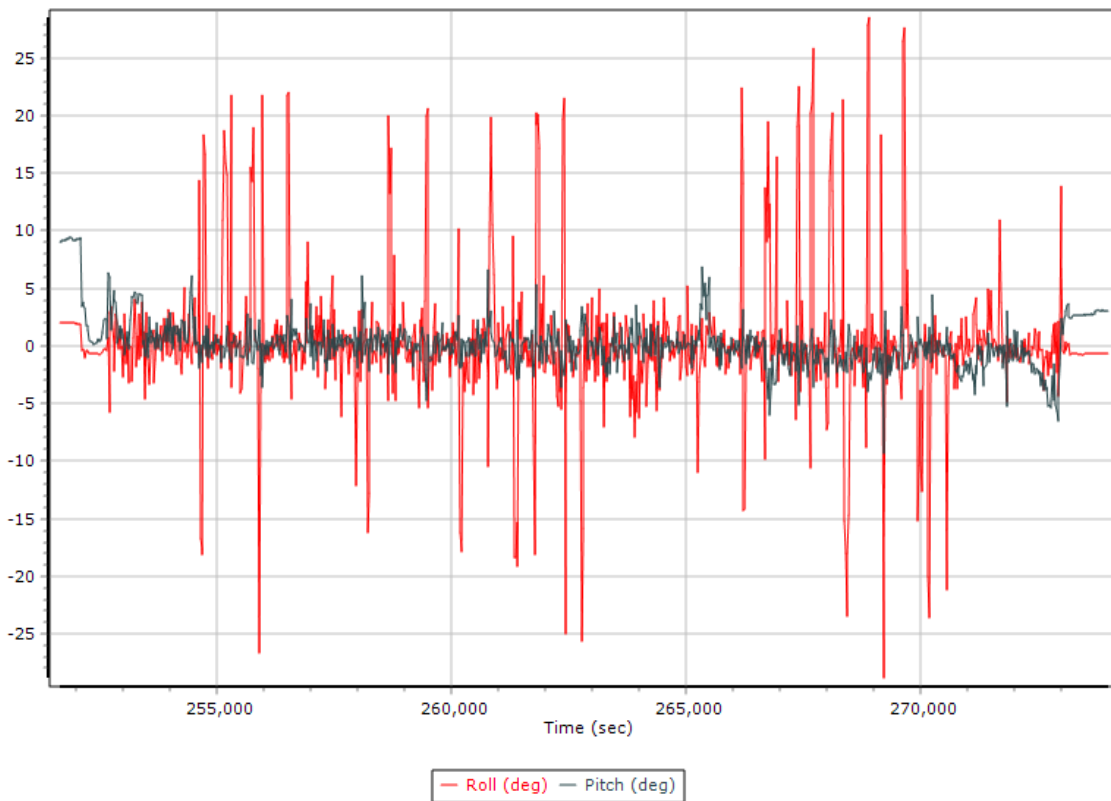
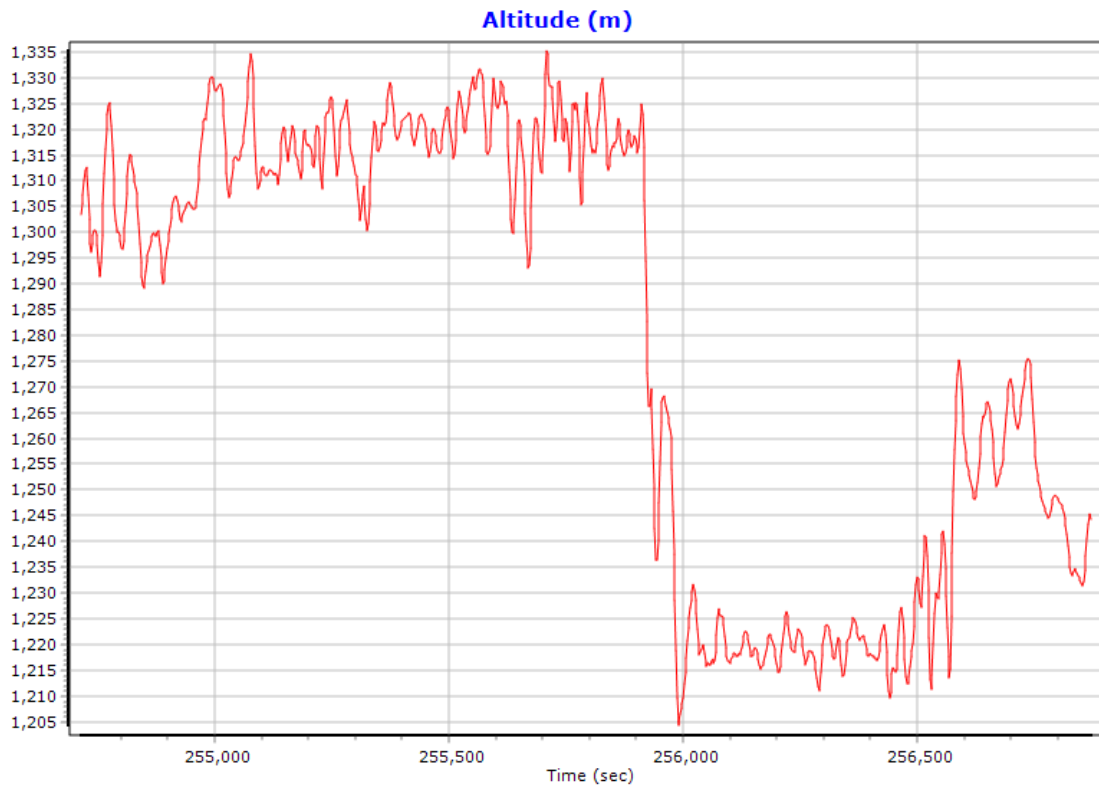


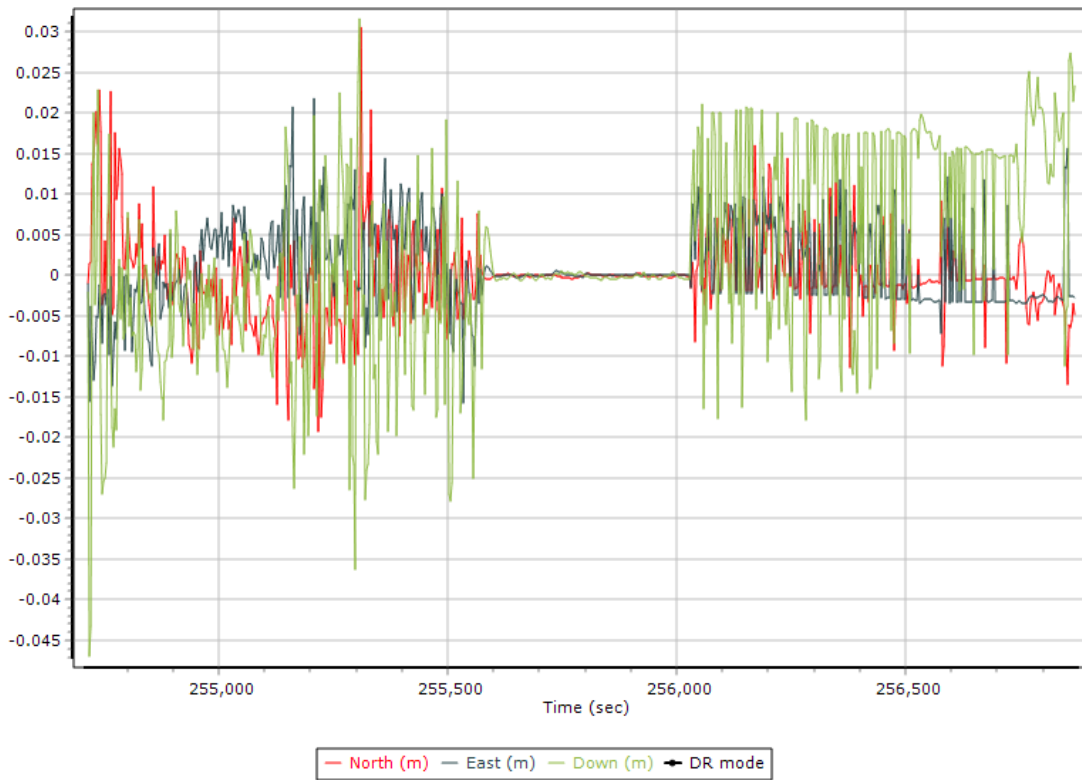
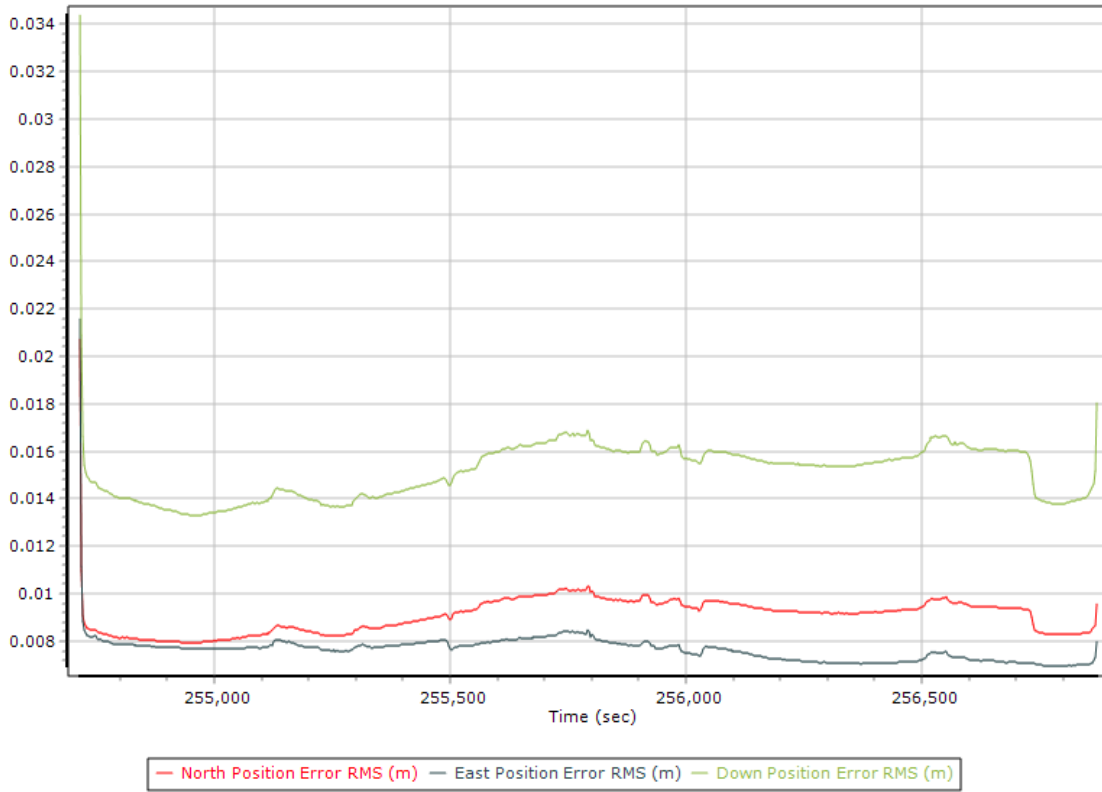
AZT18156B1

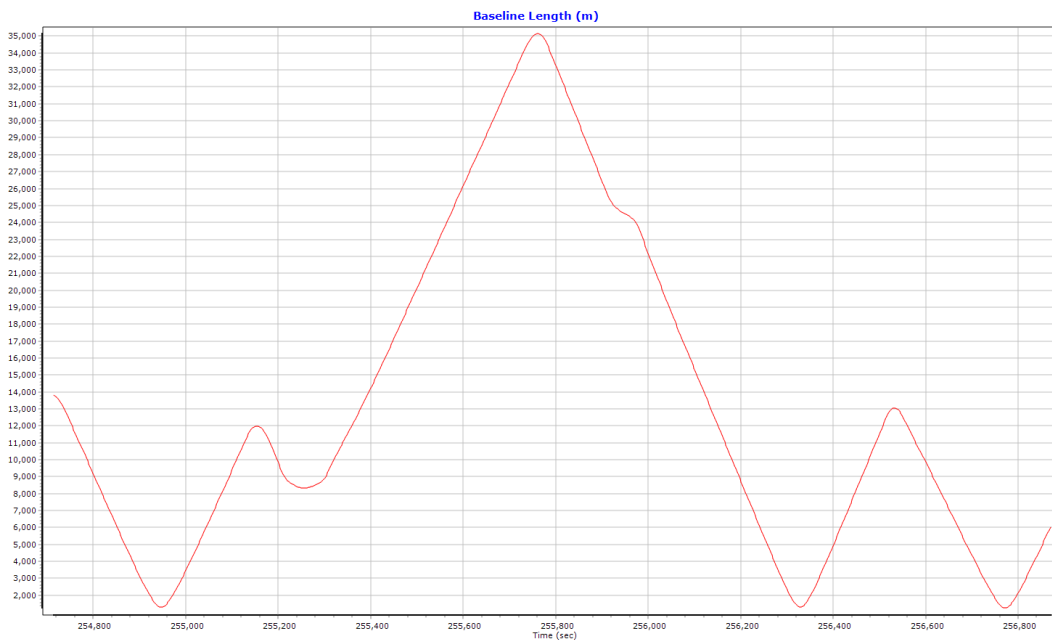
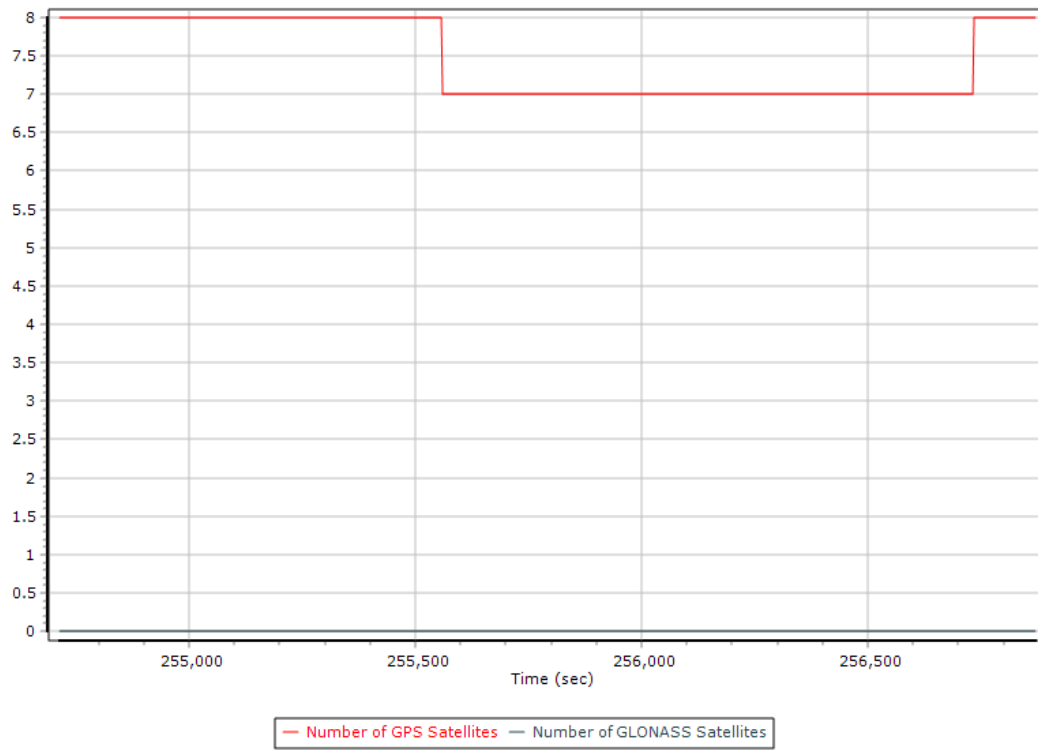


Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000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

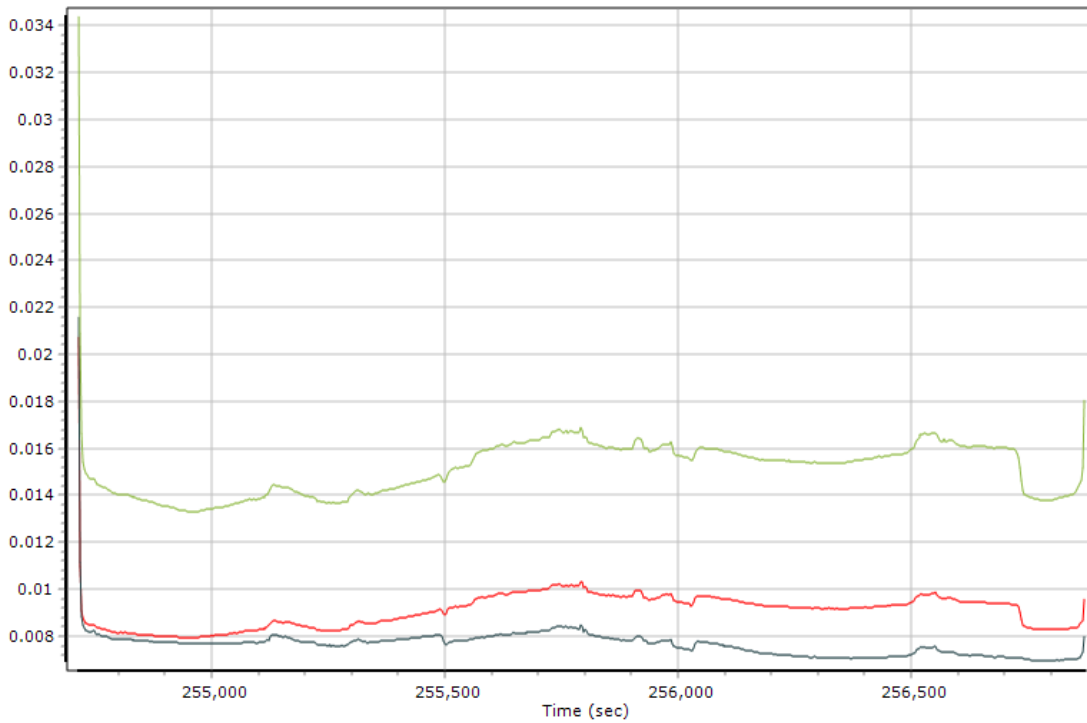
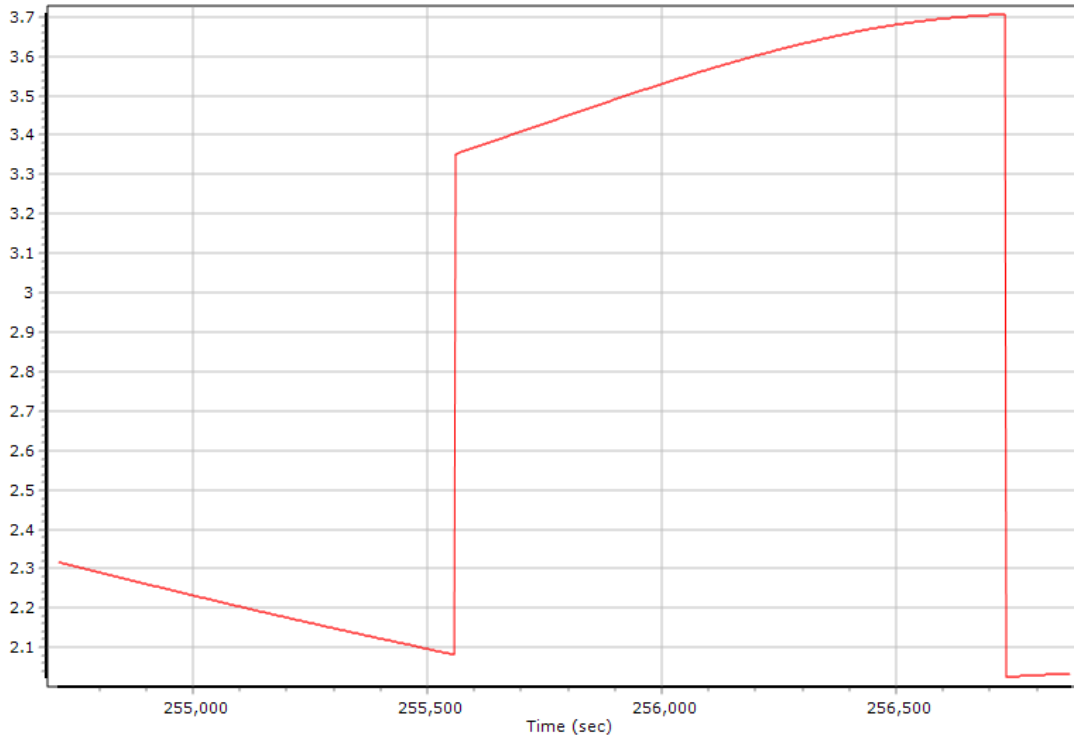
Timing									
Start	<input type="text" value="254713.175"/>								
End	<input type="text" value="256873.680"/>								
<input type="checkbox"/> Entire time interval									
<input checked="" type="checkbox"/> Seconds of start week									
UTC Offset	<input type="text" value="18.000"/>								
	<table border="1"><thead><tr><th>Data</th><th>Incr. (sec)</th></tr></thead><tbody><tr><td>Output Record</td><td>0.005000</td></tr><tr><td>IMU</td><td>0.005000</td></tr><tr><td>Primary GNSS</td><td>1.000000</td></tr></tbody></table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000
Data	Incr. (sec)								
Output Record	0.005000								
IMU	0.005000								
Primary GNSS	1.000000								



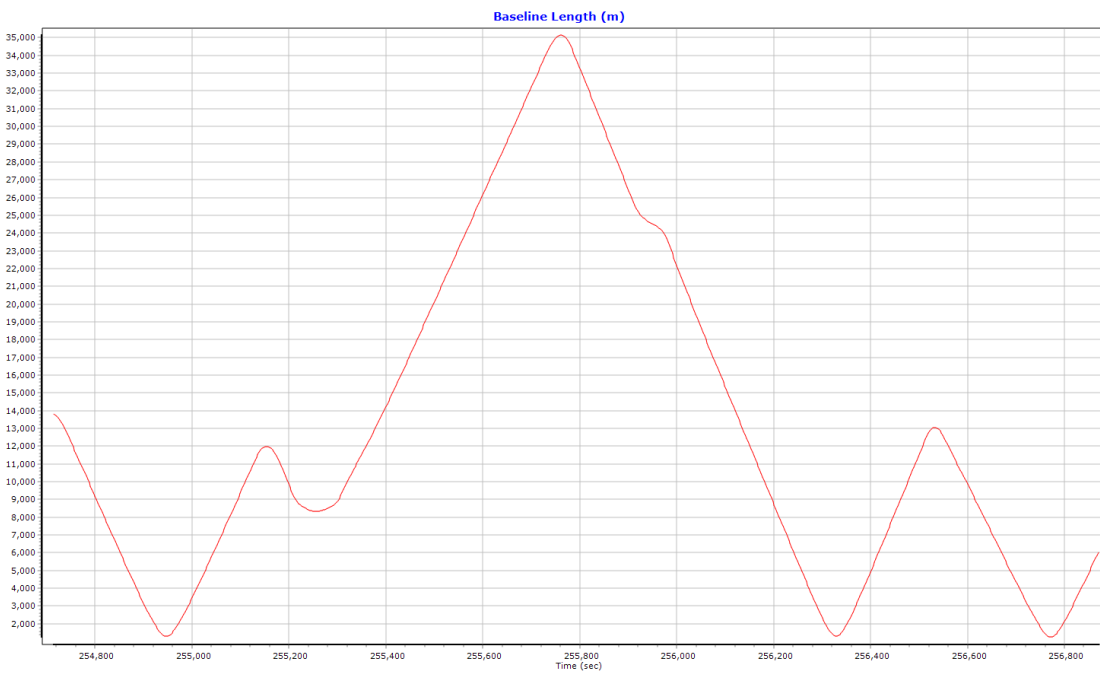
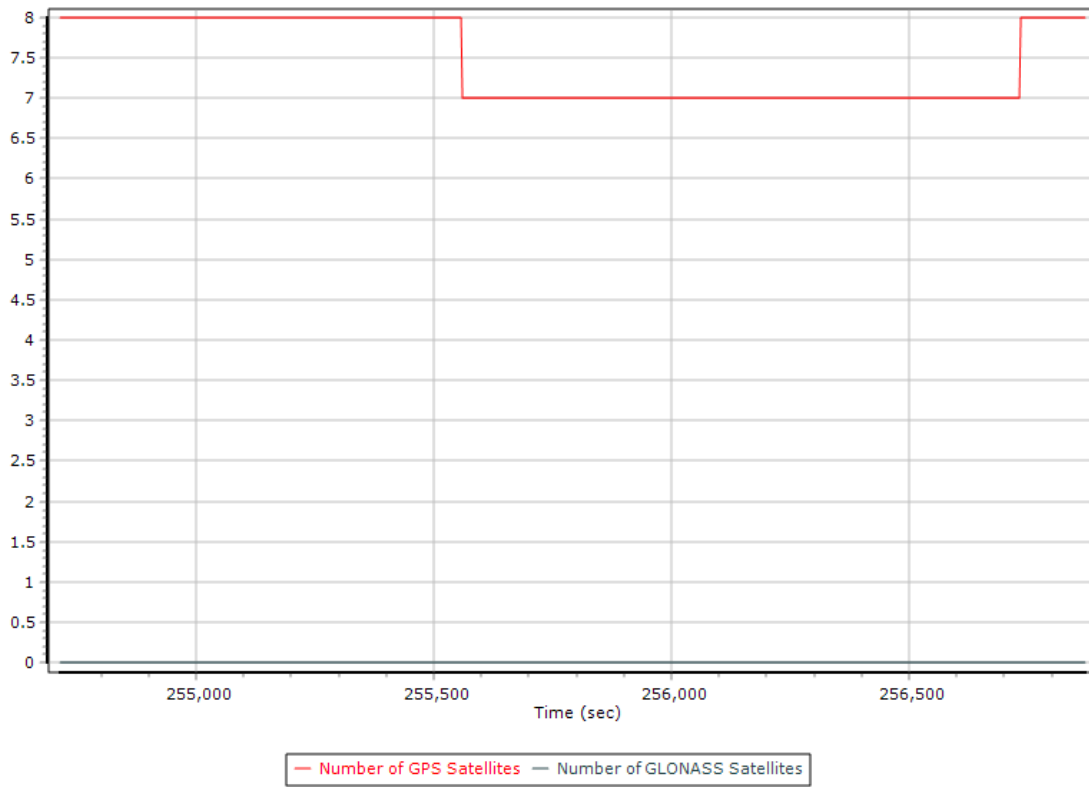


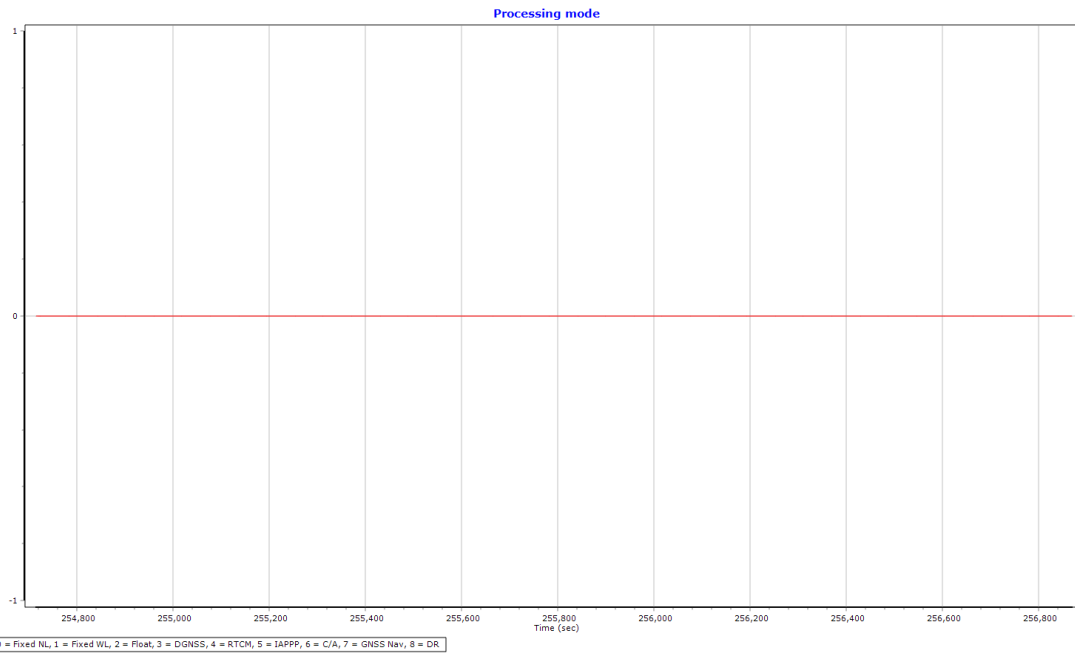
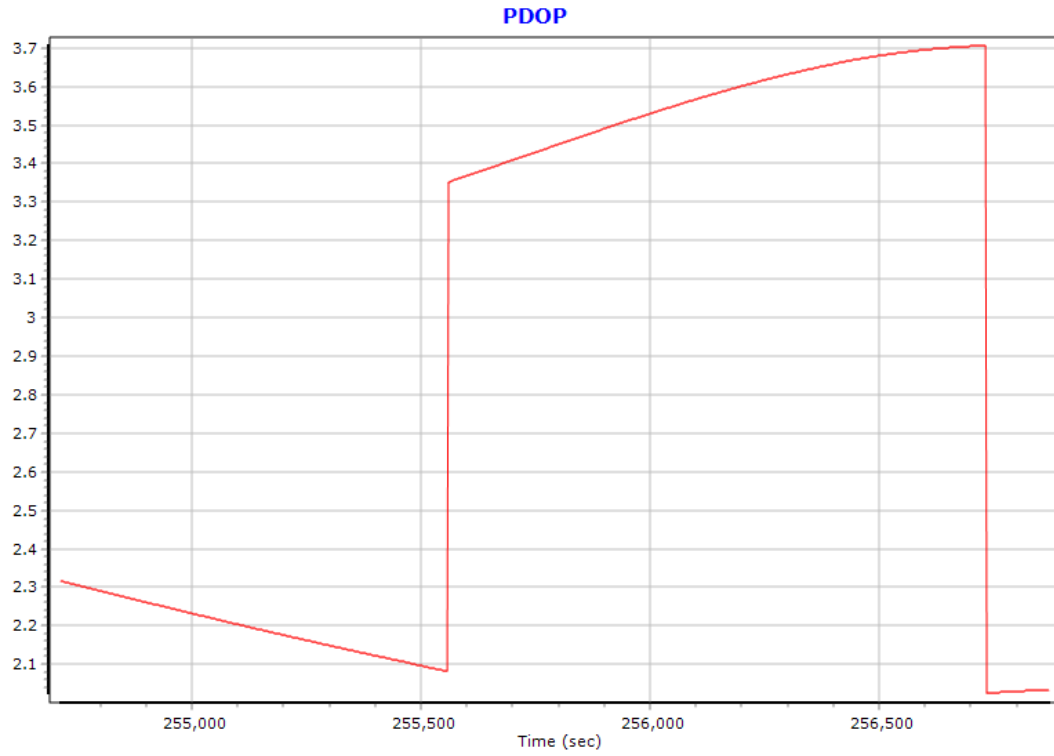


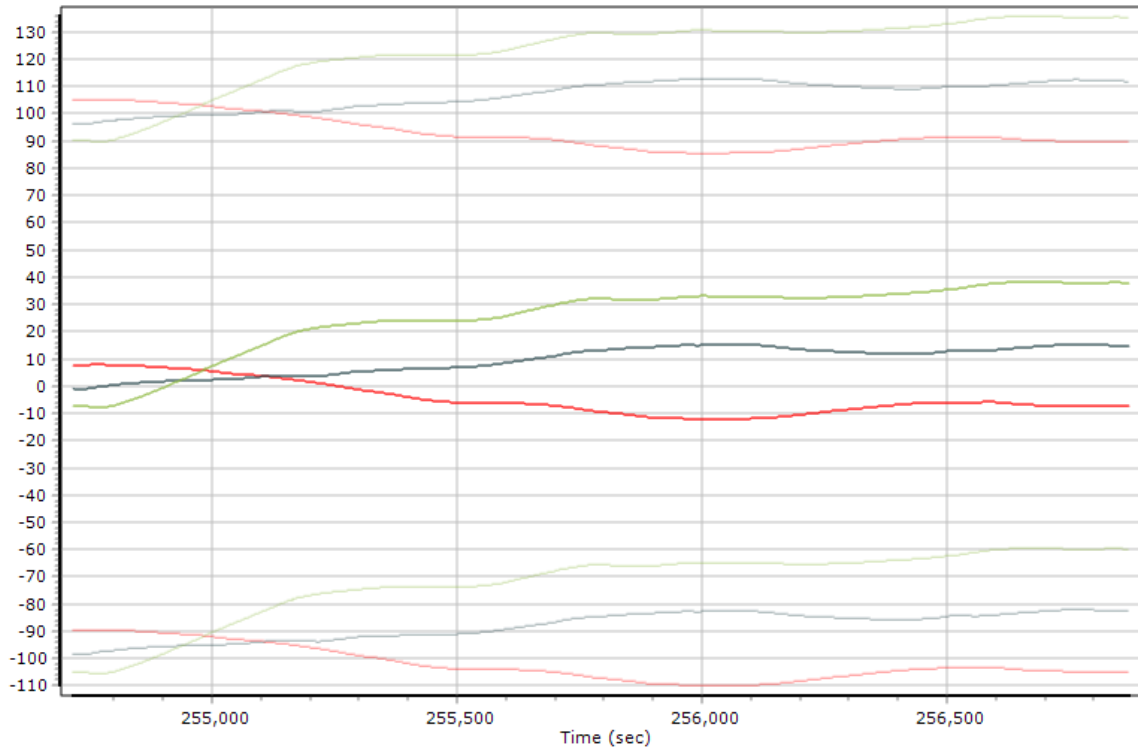
PDOP



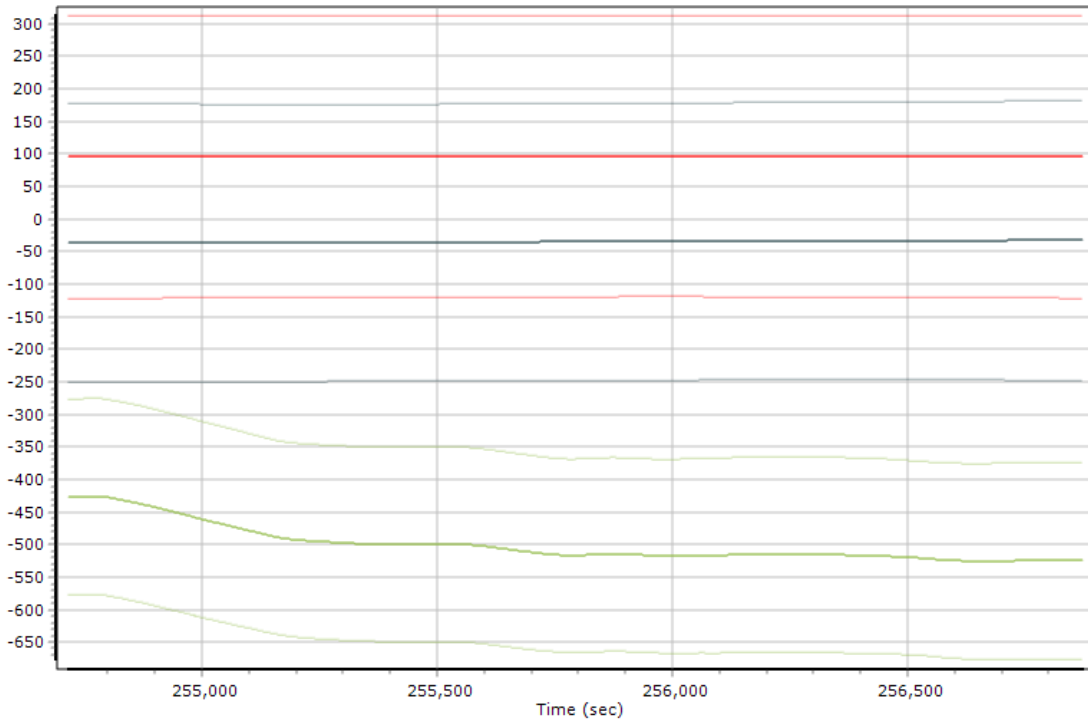
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



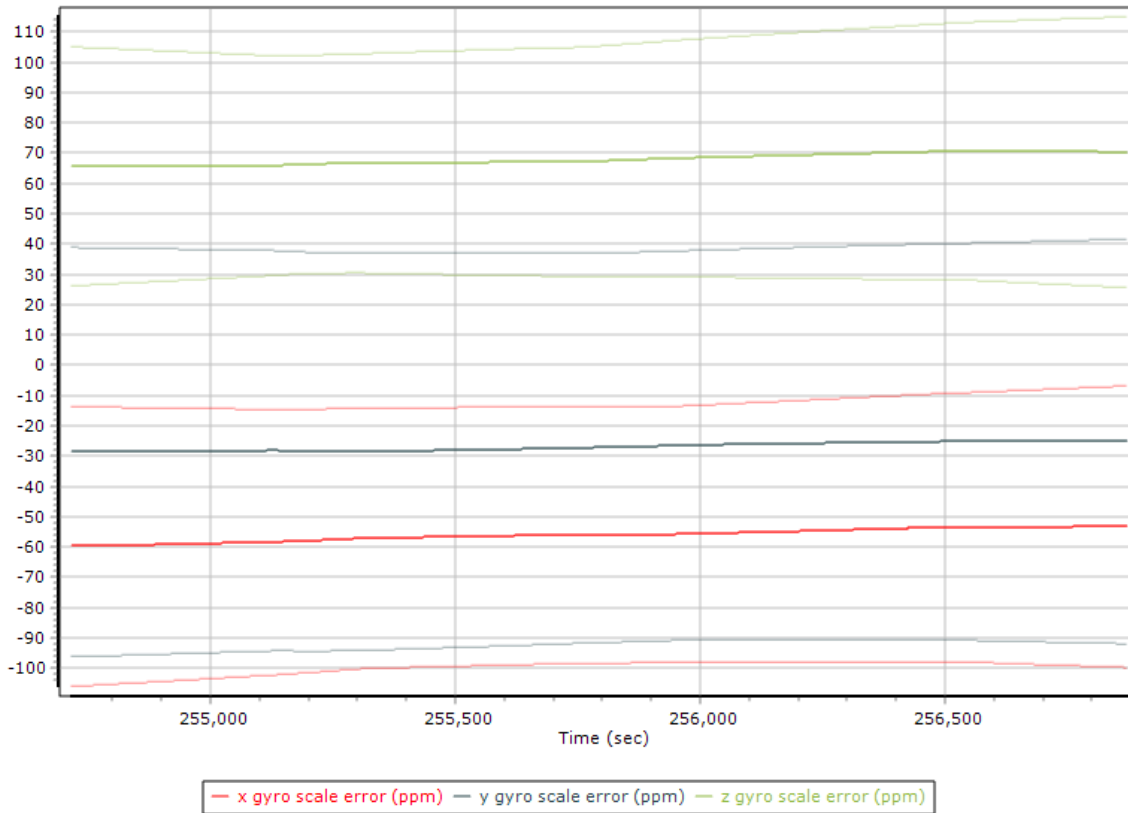
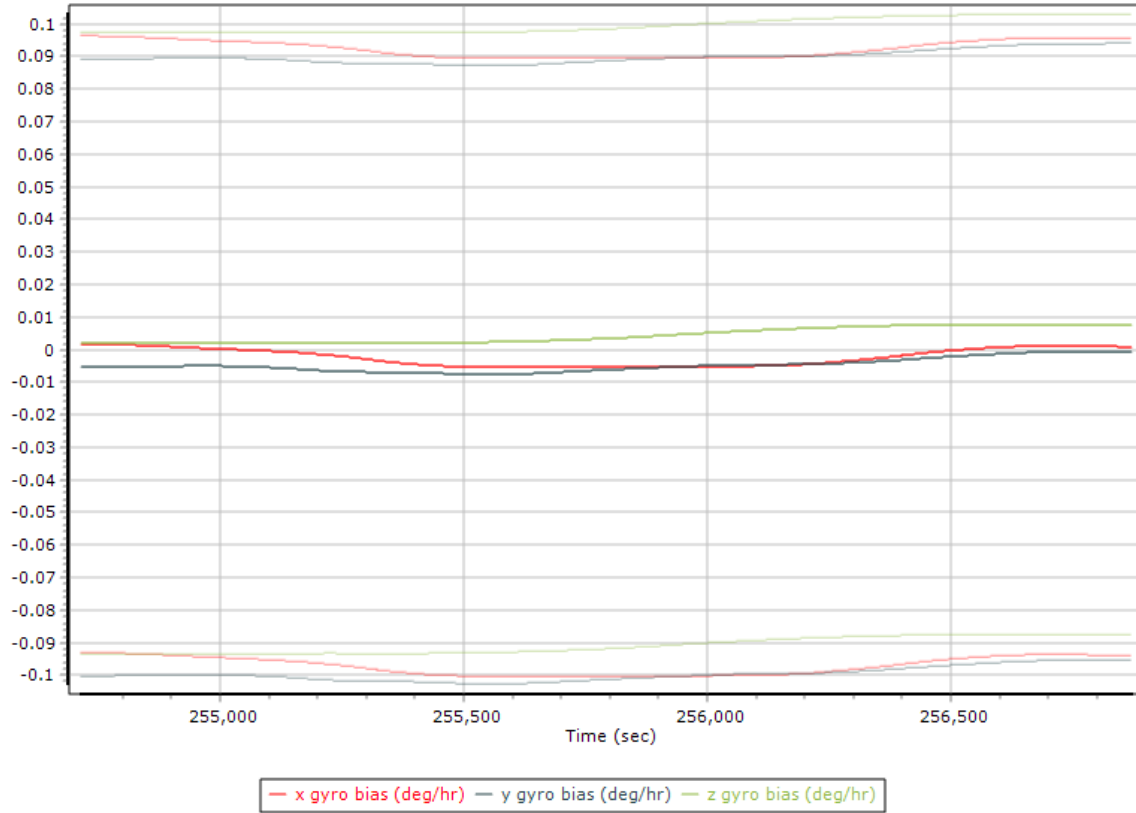




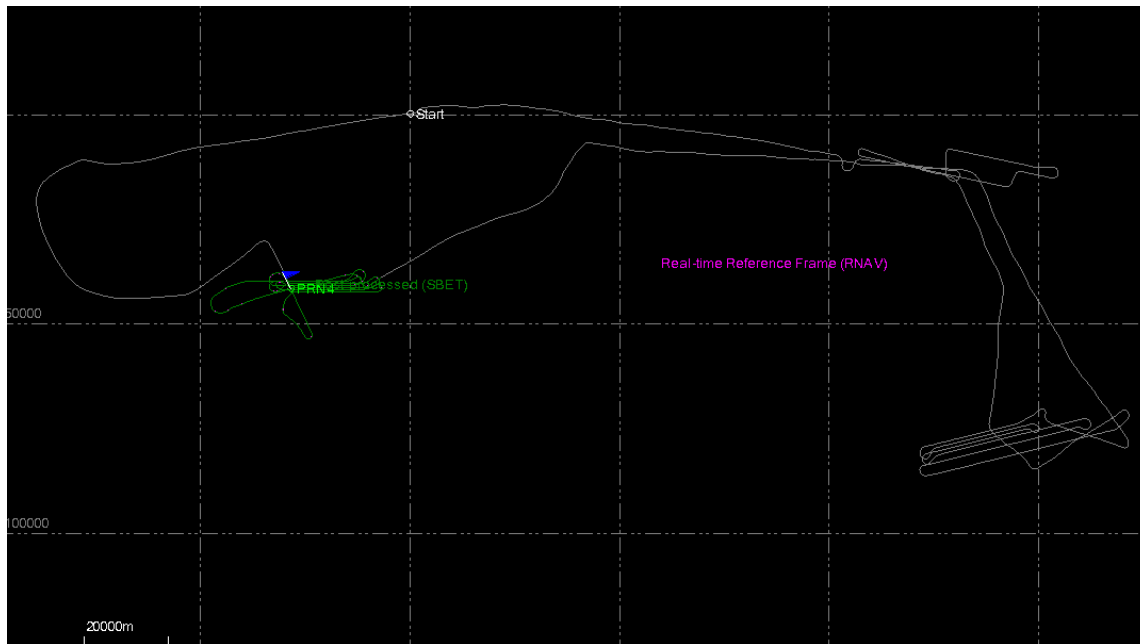
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)



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



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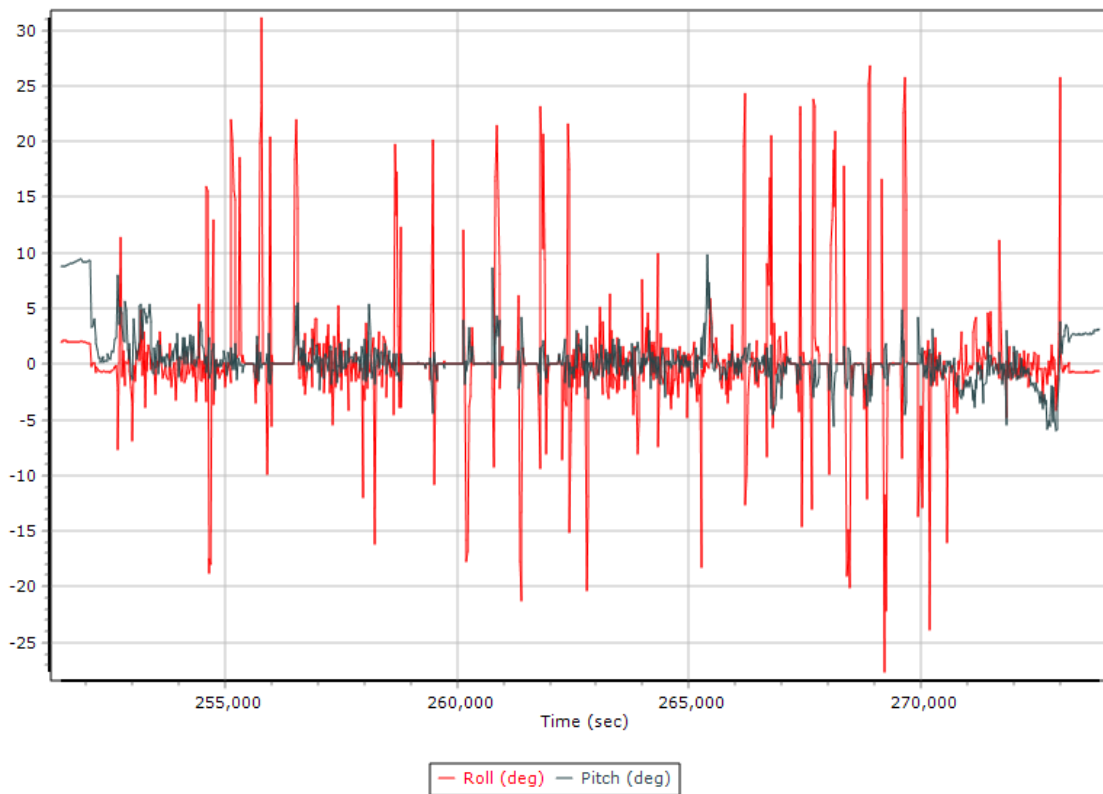
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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 max="10" min="0.03" type="range" value="0.03"/>		
	<p><3cm 10cm 50cm 1m 10m</p>		

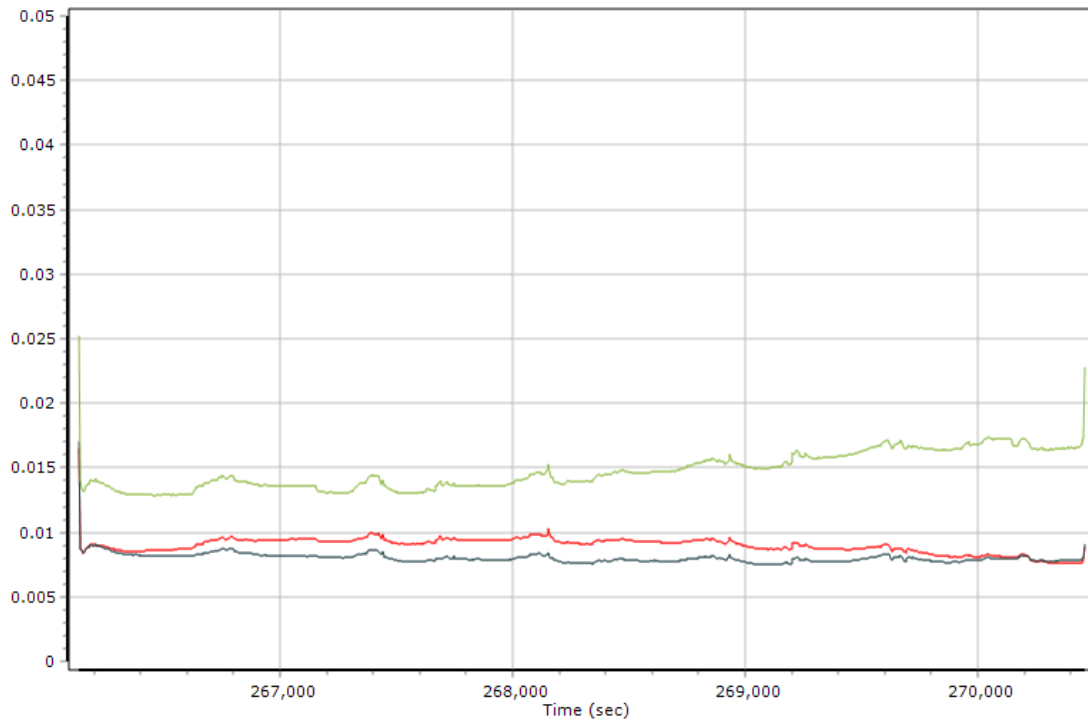
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

Timing

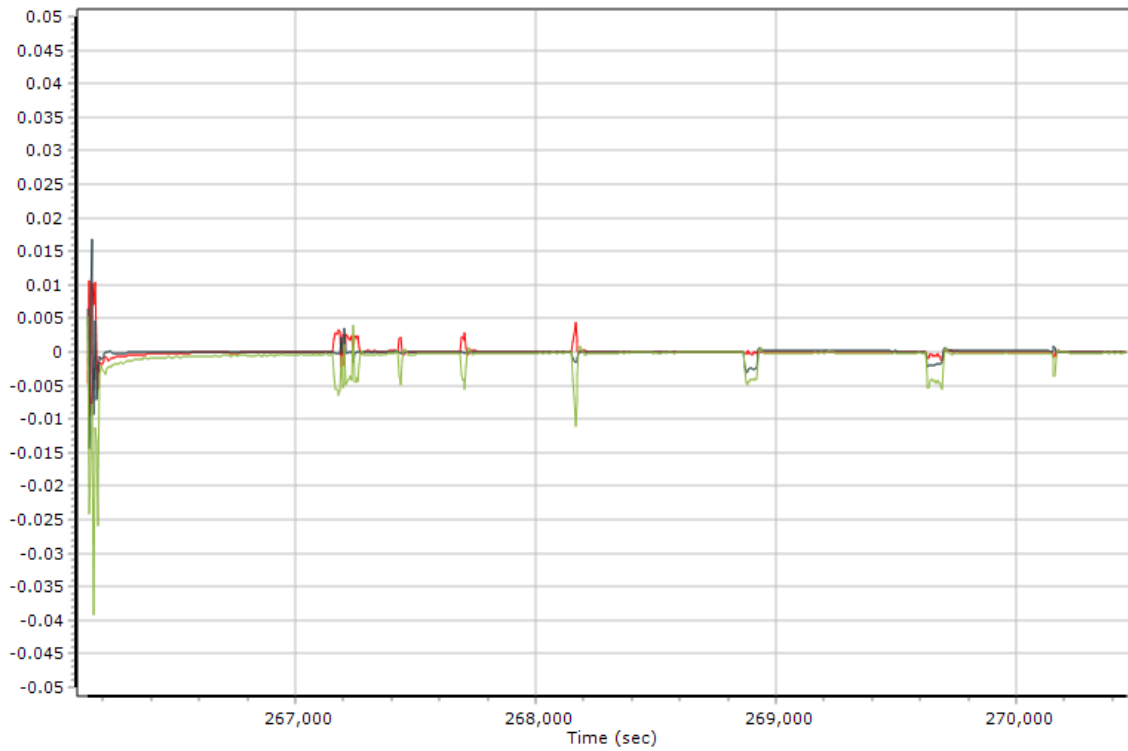
Start	266133.292	Data	Incr. (sec)
End	270464.303	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset 18.000

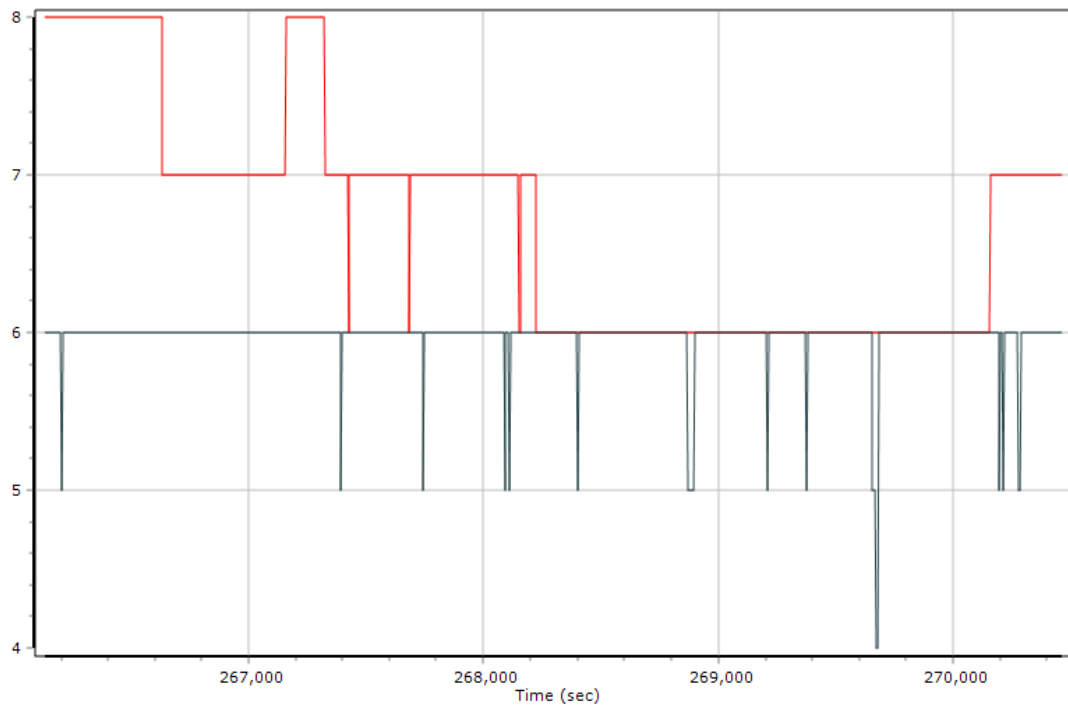




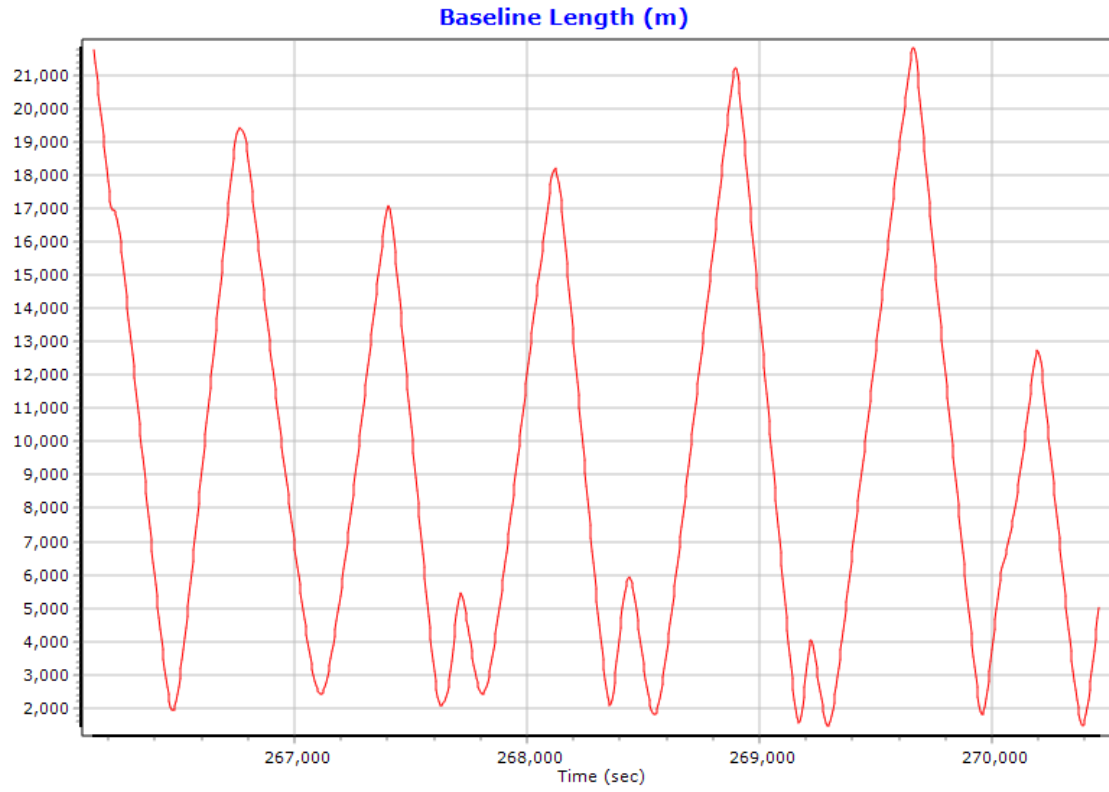
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



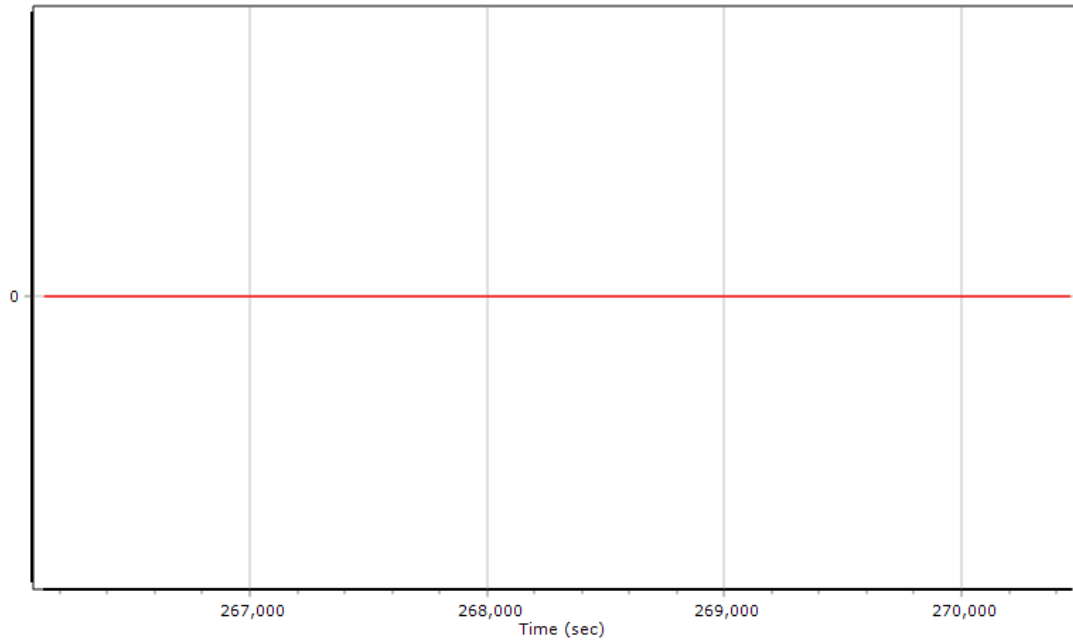
— North (m) — East (m) — Down (m) — DR mode



— Number of GPS Satellites — Number of GLONASS Satellites

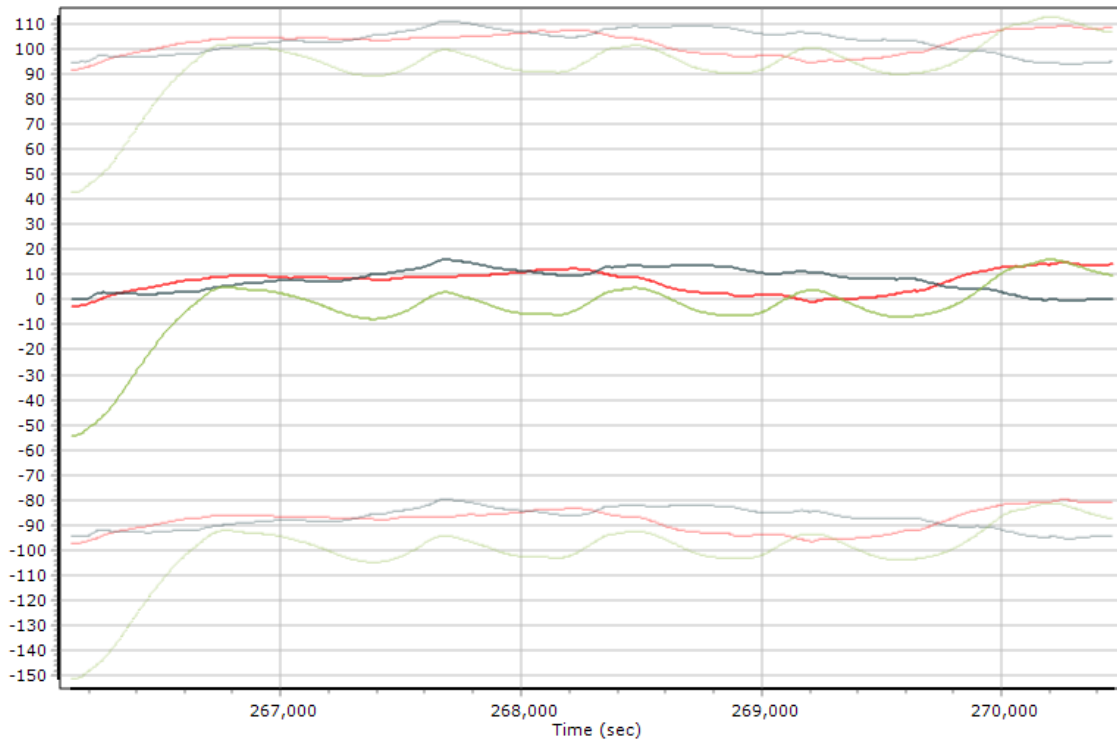


Processing Mode

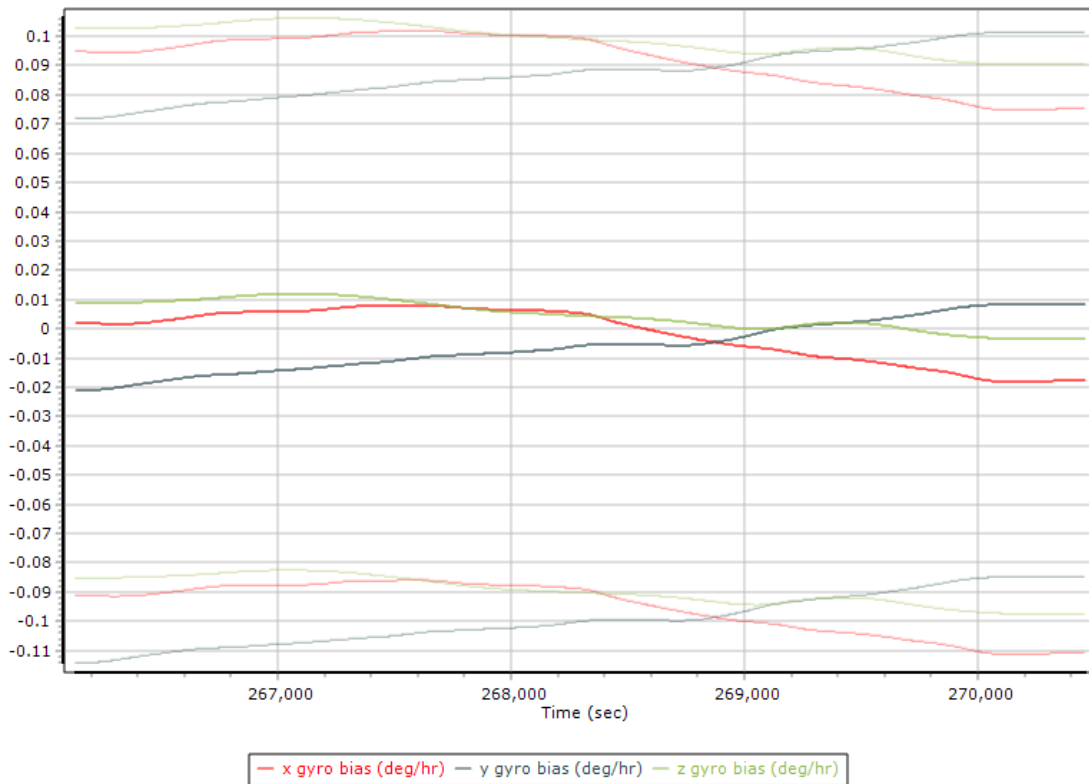
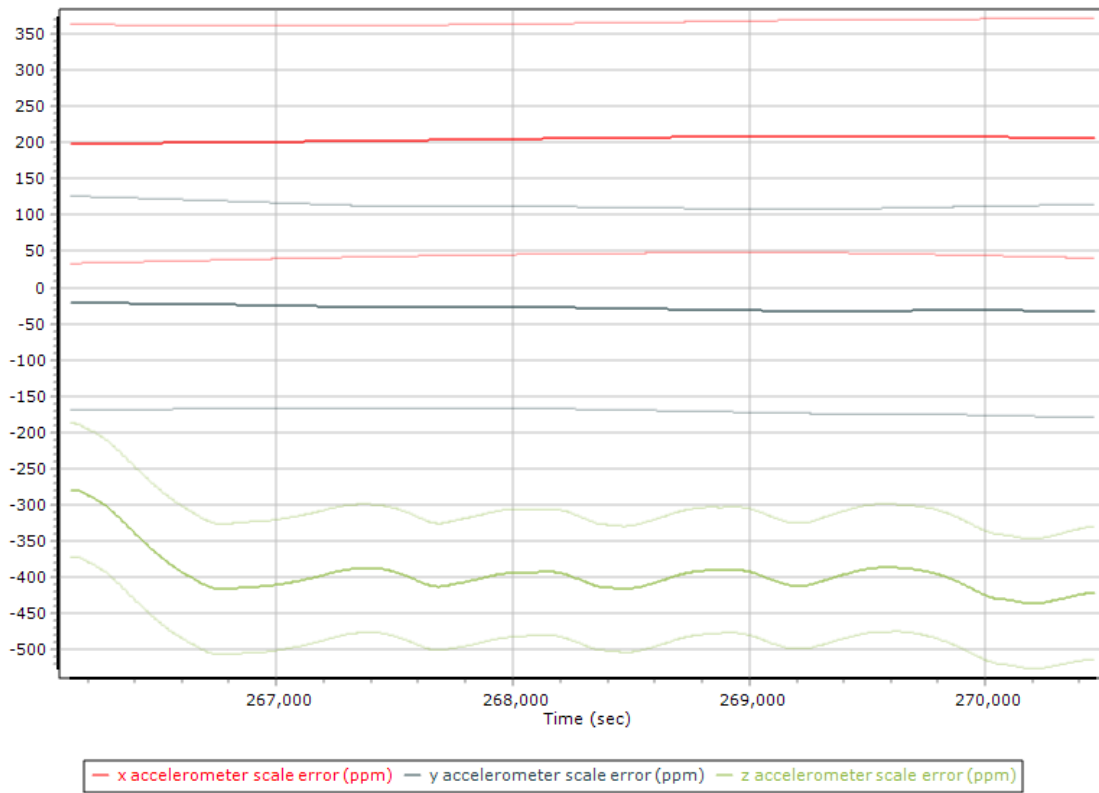


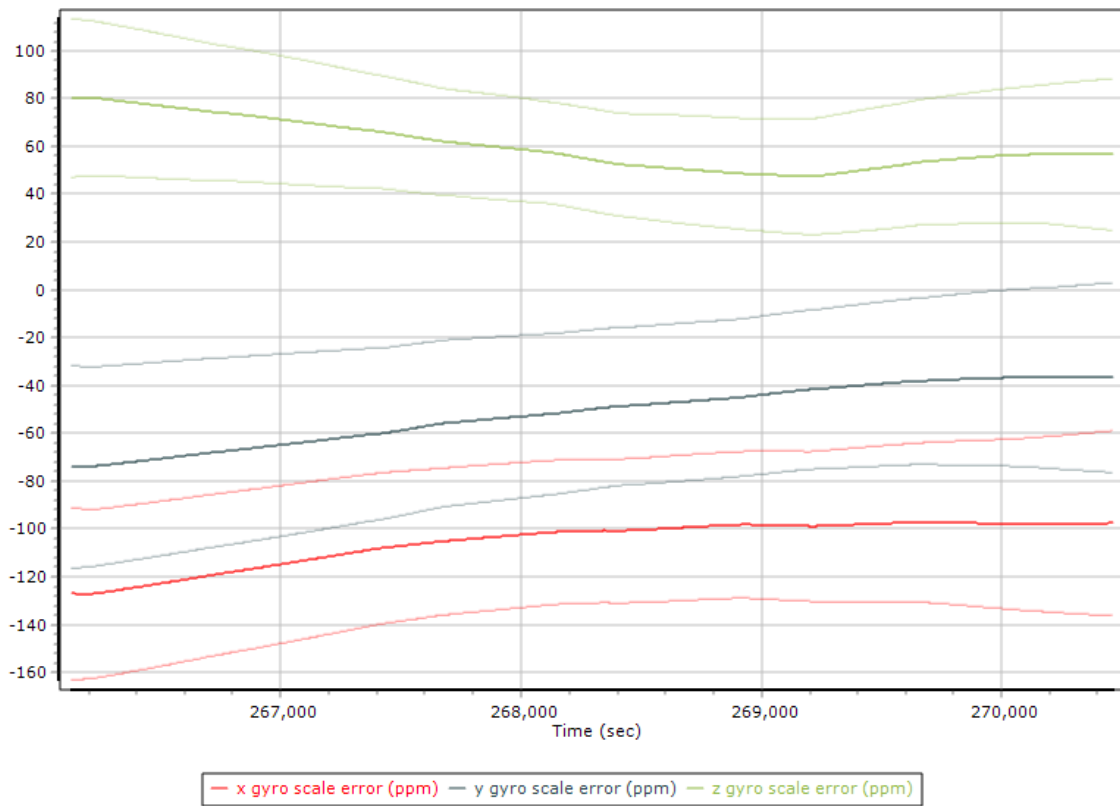
Forward Reverse

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

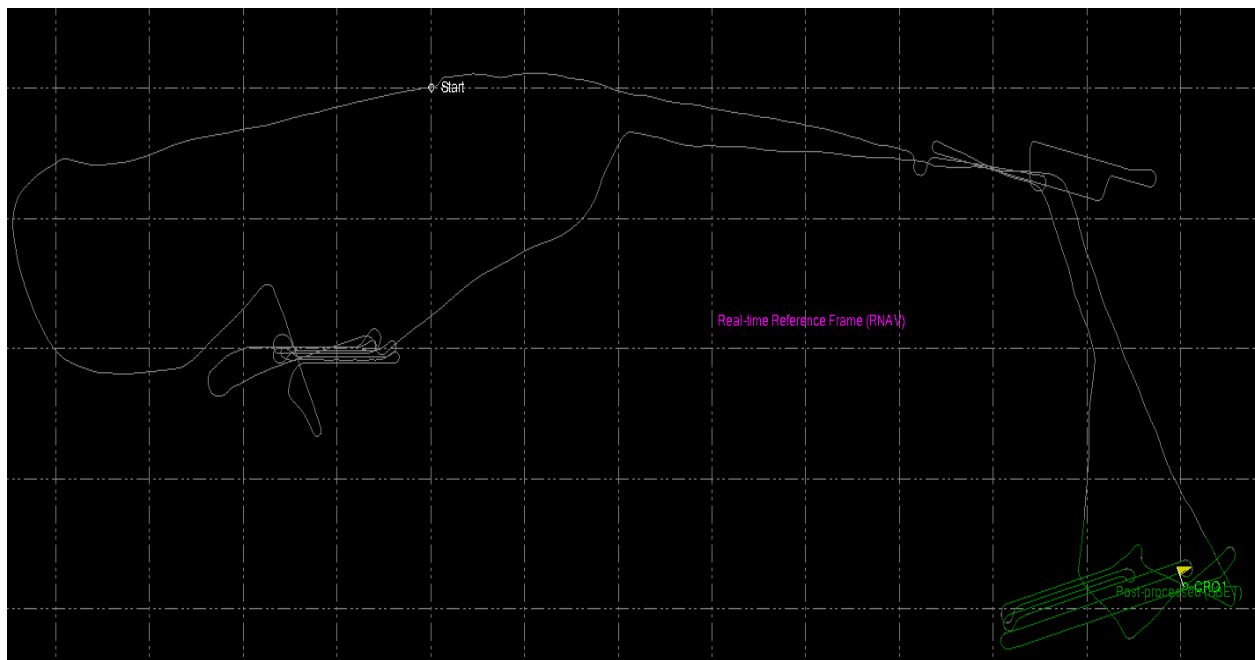


— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)





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Stabilized Mount to IMU Lever Arm

X:

Y:

Z:

Stabilized Mount to IMU Mounting Angles

X:

Y:

Z:

Stabilized Mount to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

Aircraft to Stabilized Mount Mounting Angles

X:

Y:

Z:

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

Timing

Start:

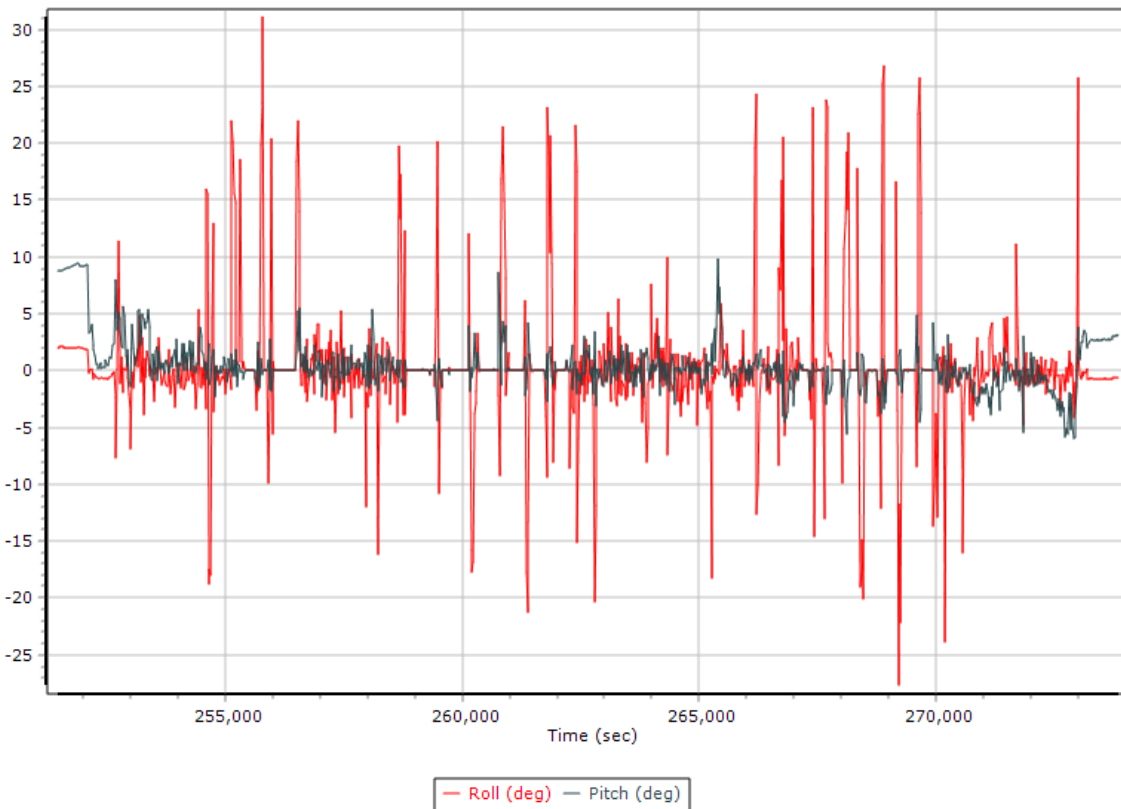
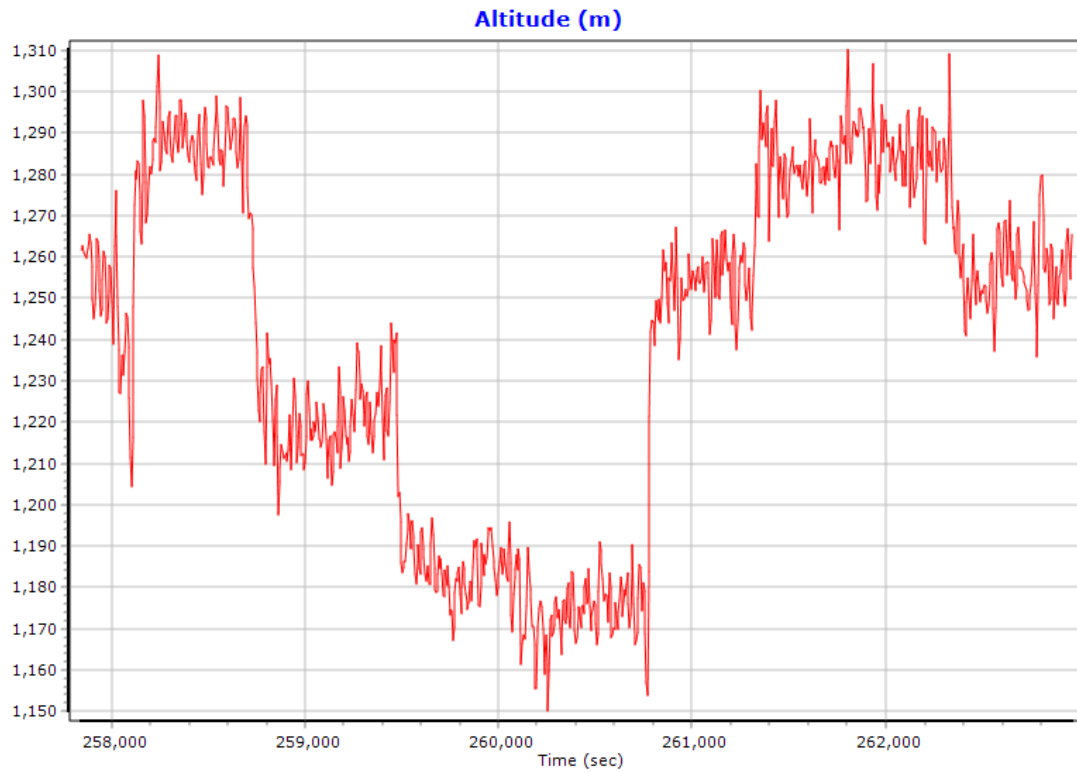
End:

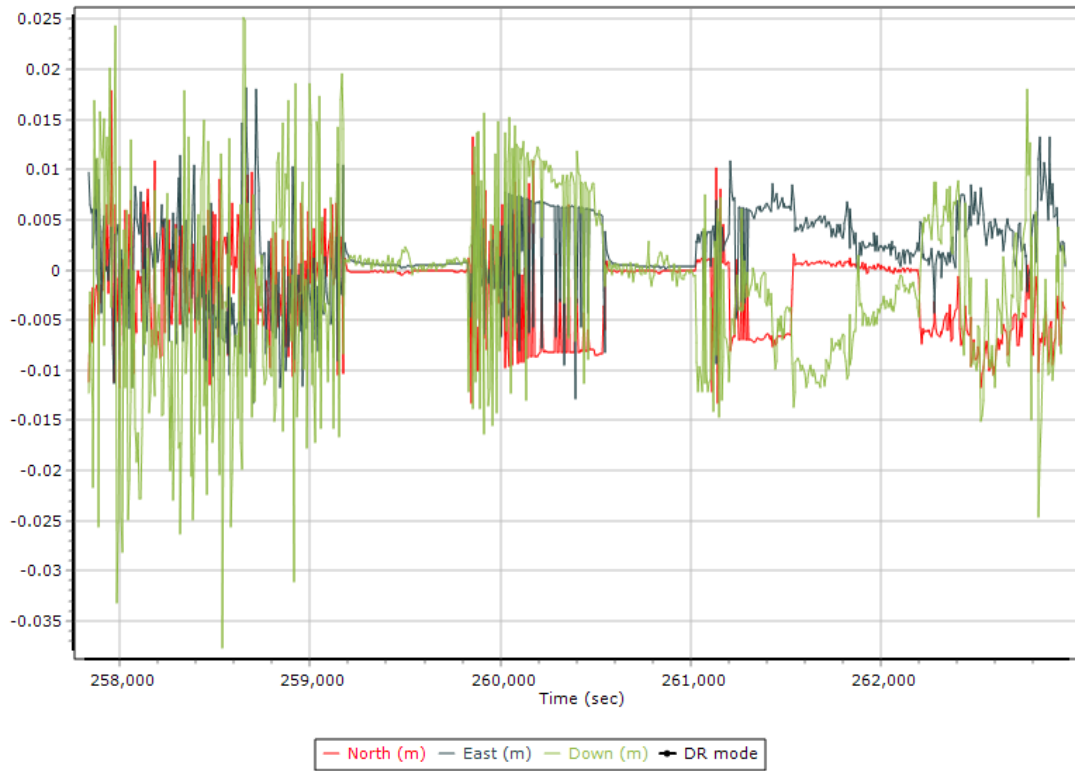
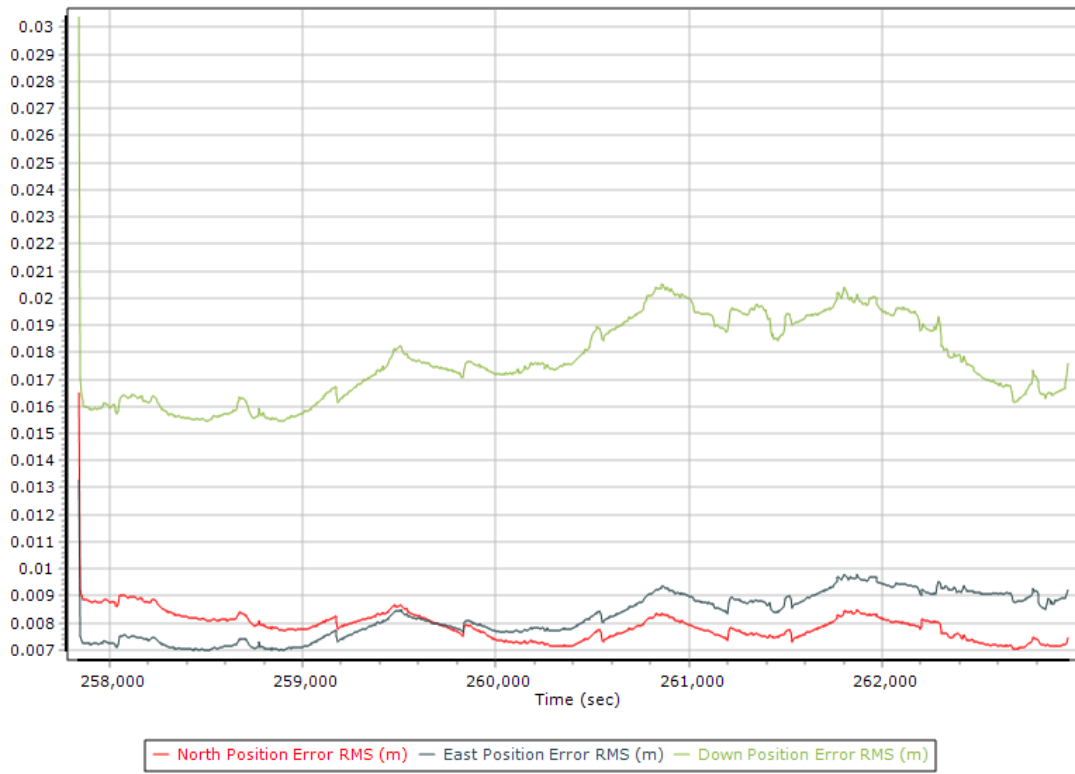
Entire time interval

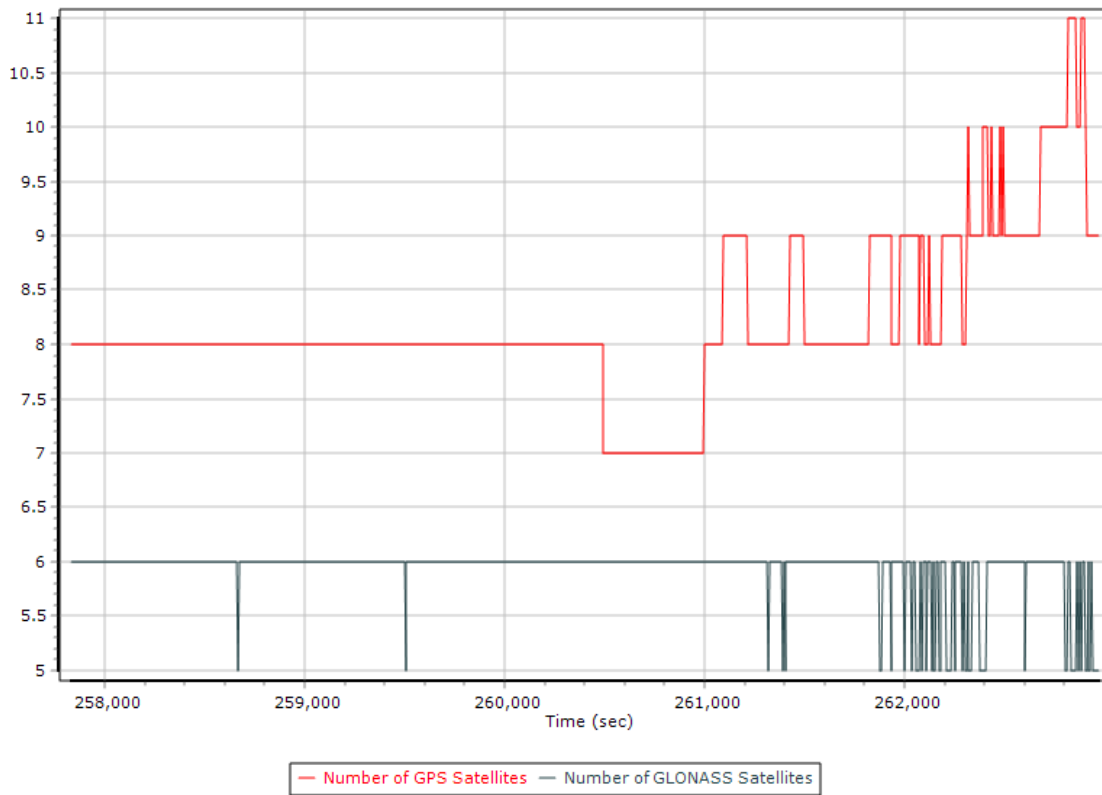
Seconds of start week

UTC Offset:

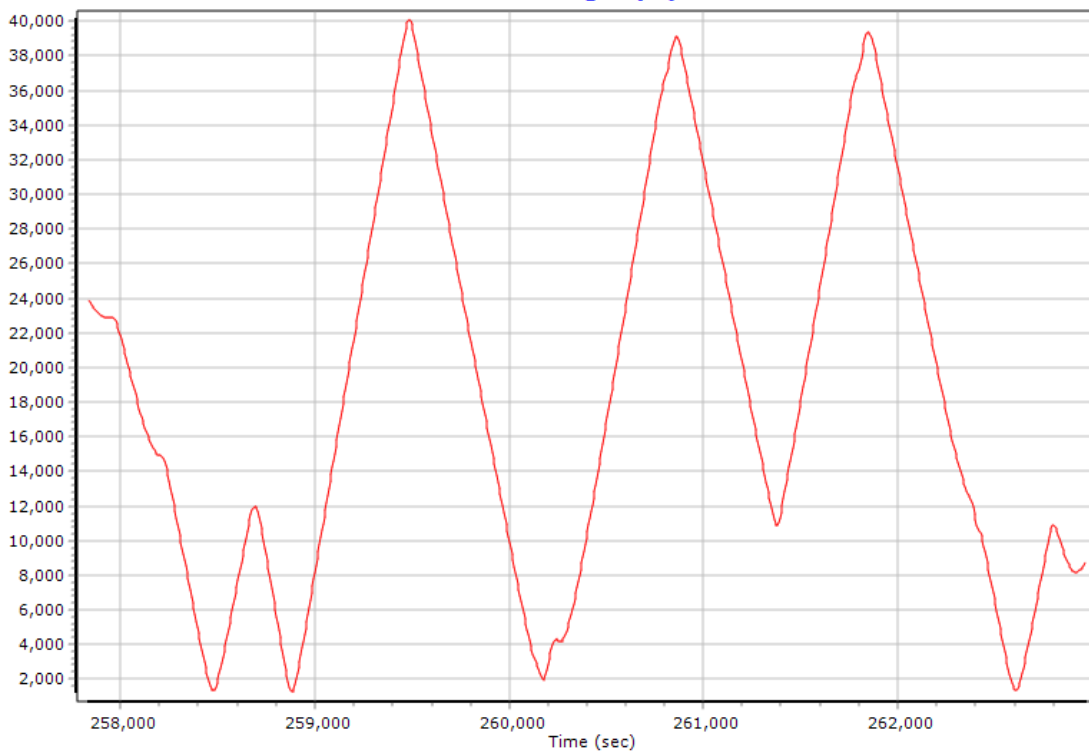
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

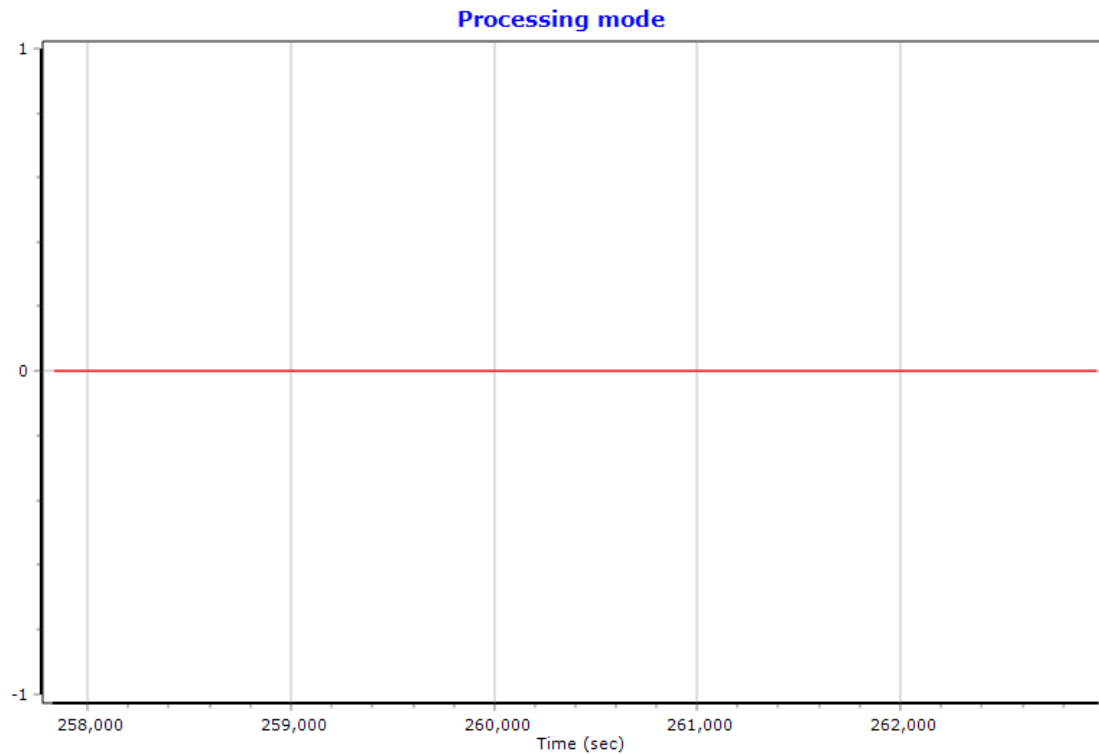
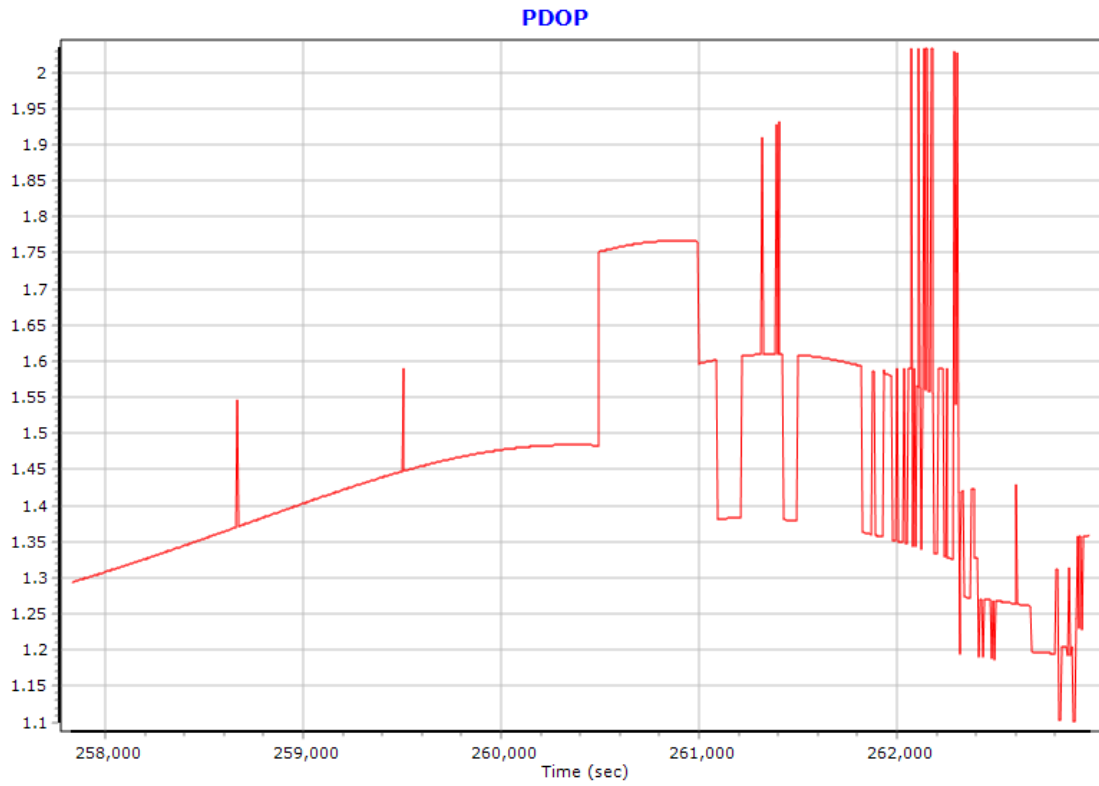




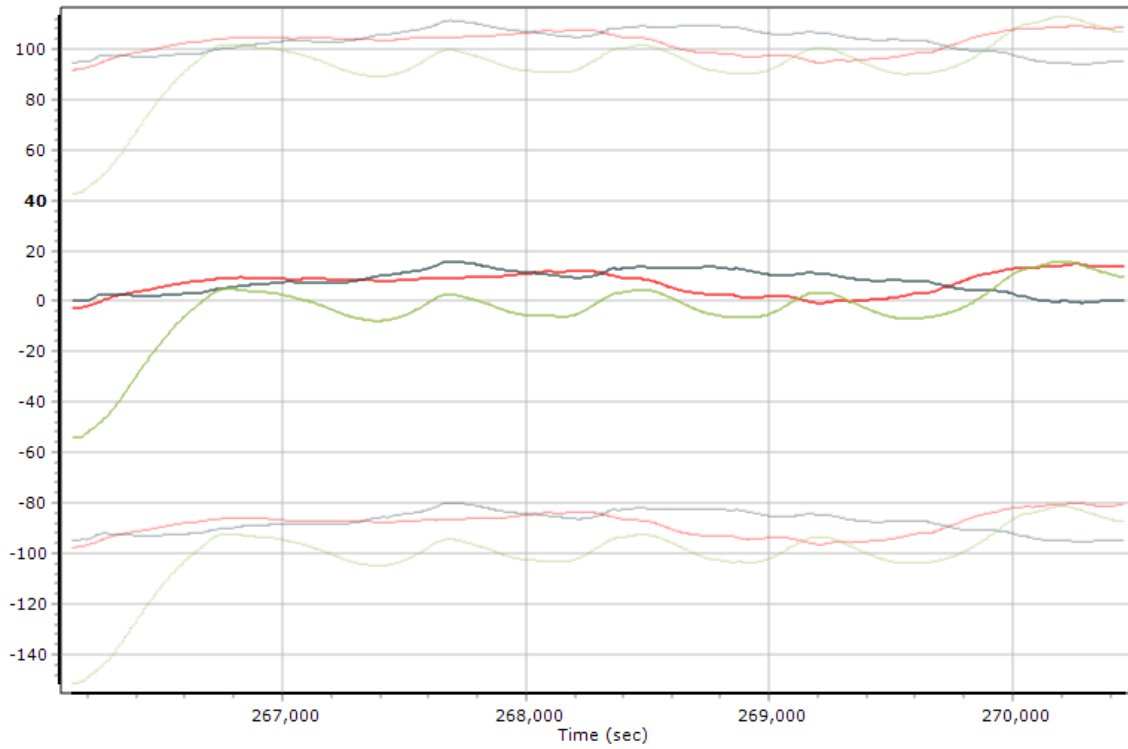


Baseline Length (m)

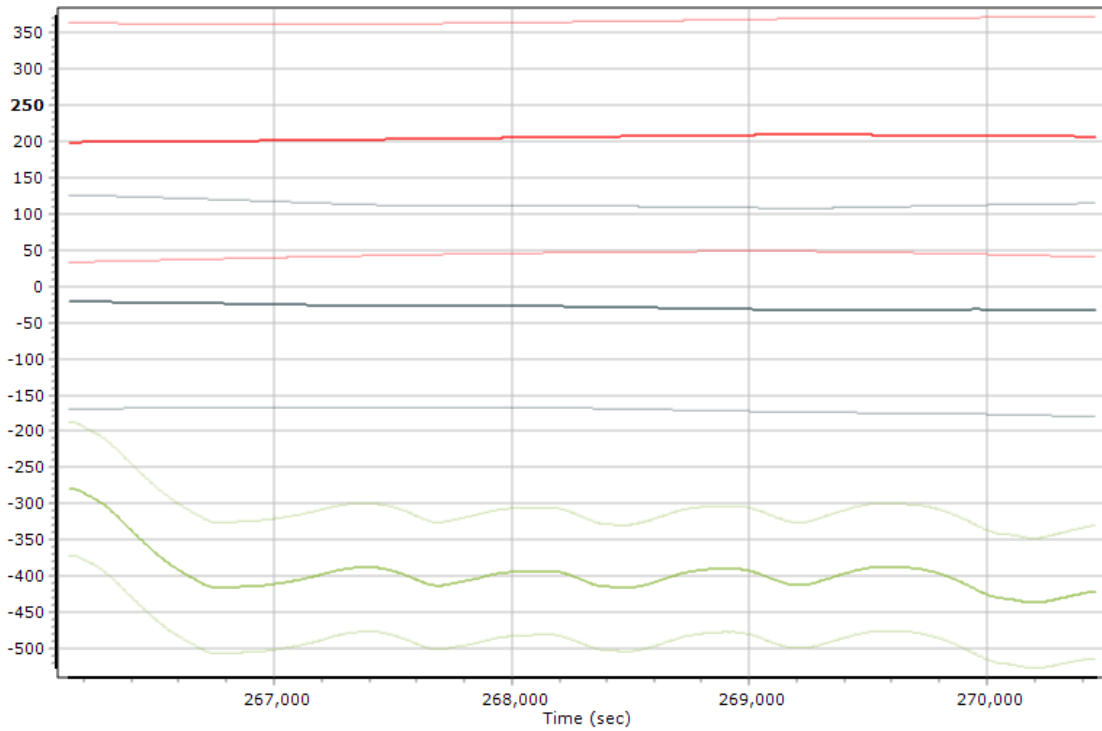




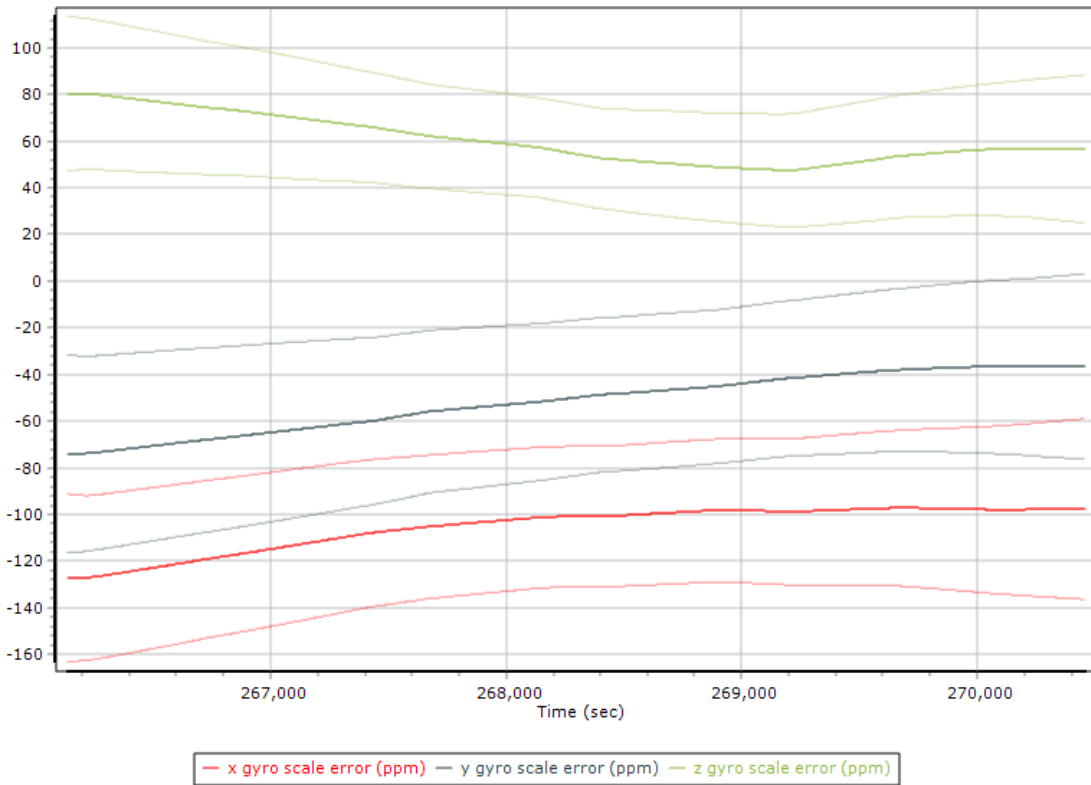
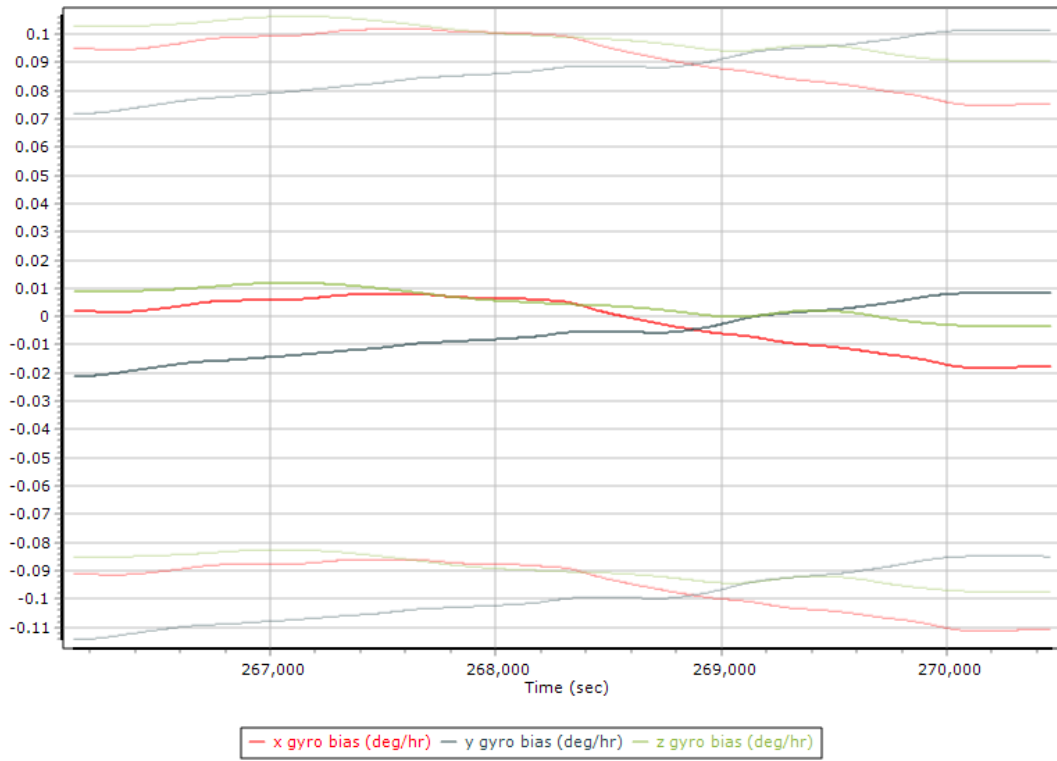
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



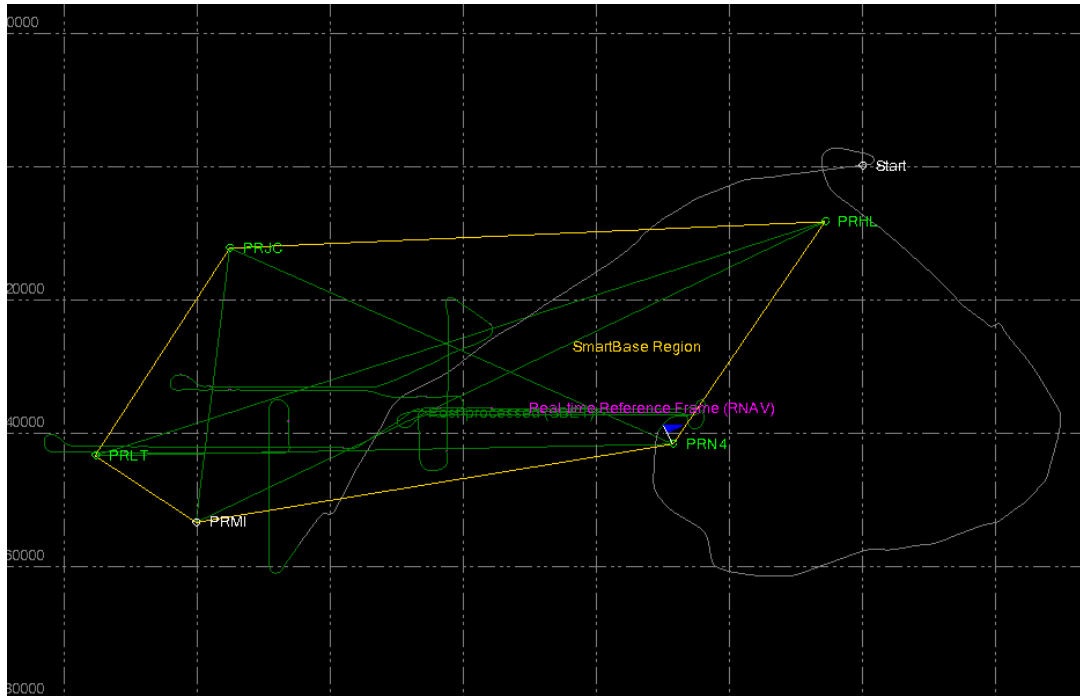
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



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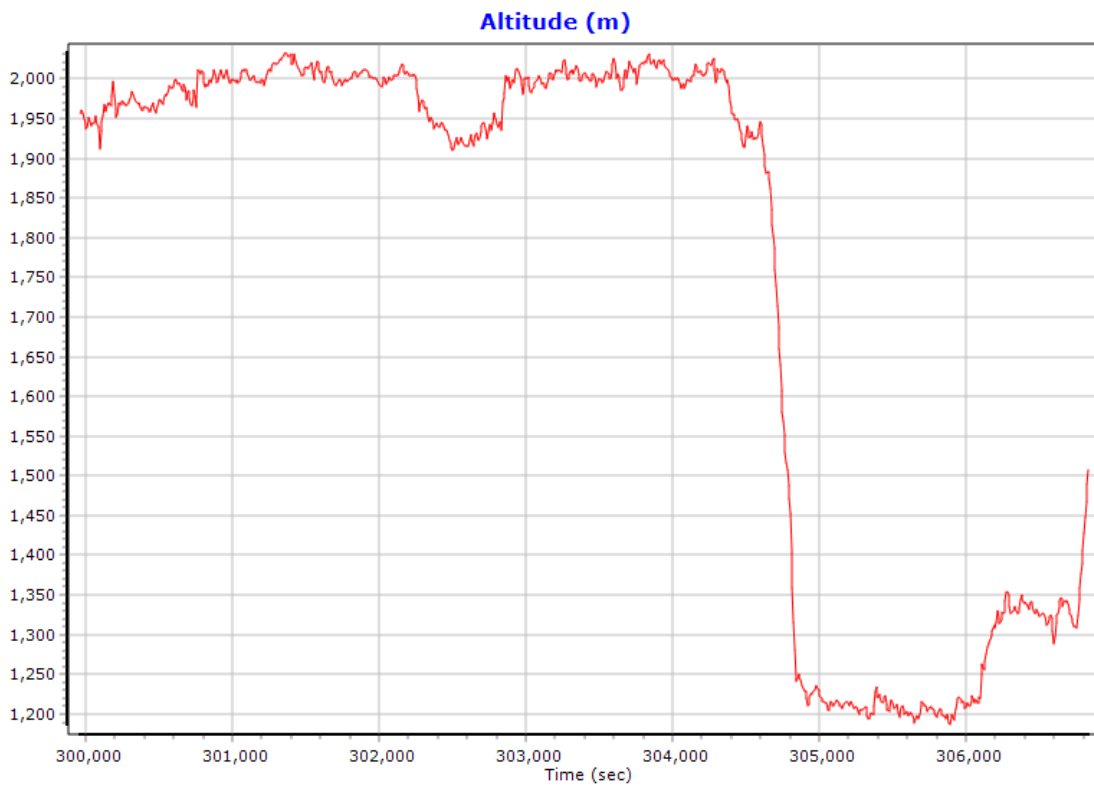
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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="3cm"/>		
	<3cm 10cm 50cm 1m 10m		

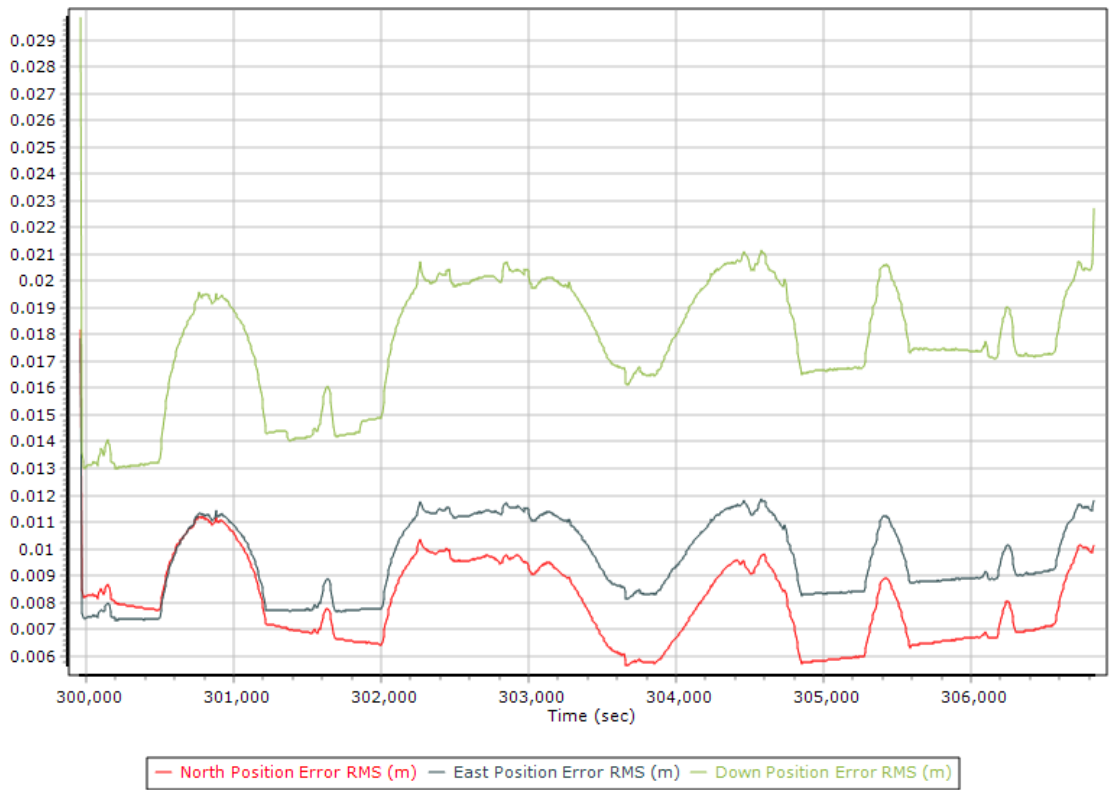
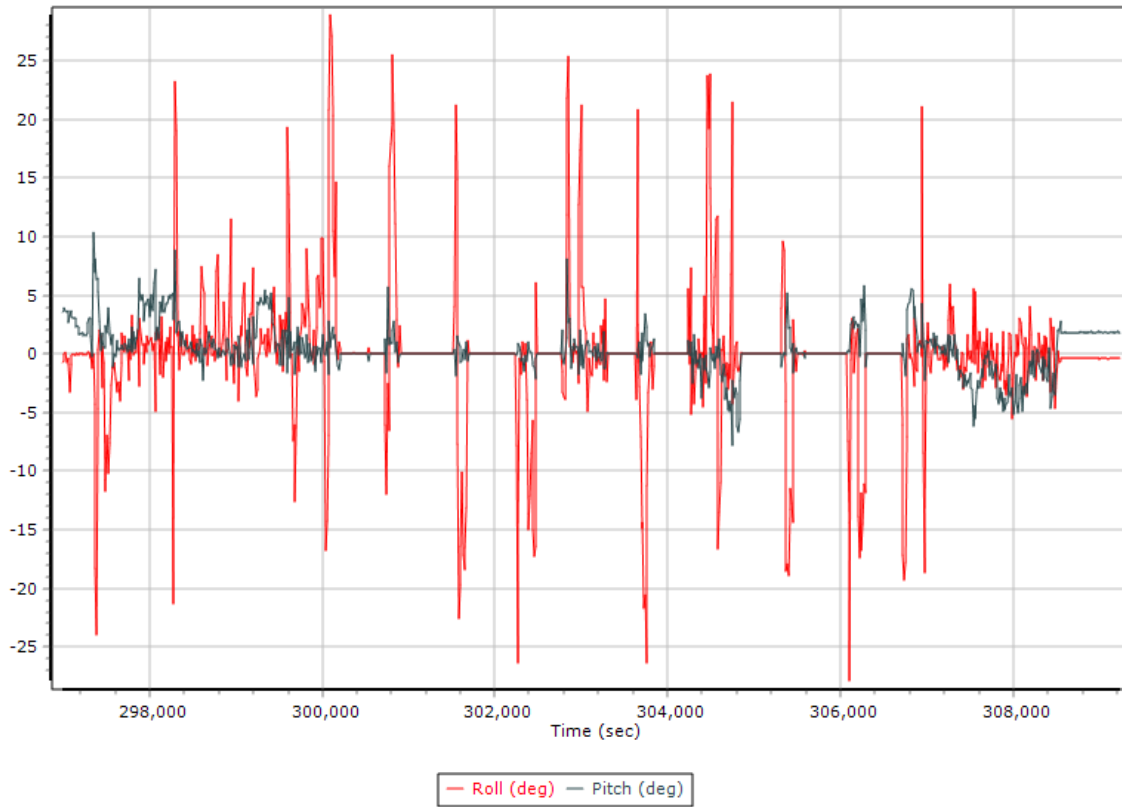
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

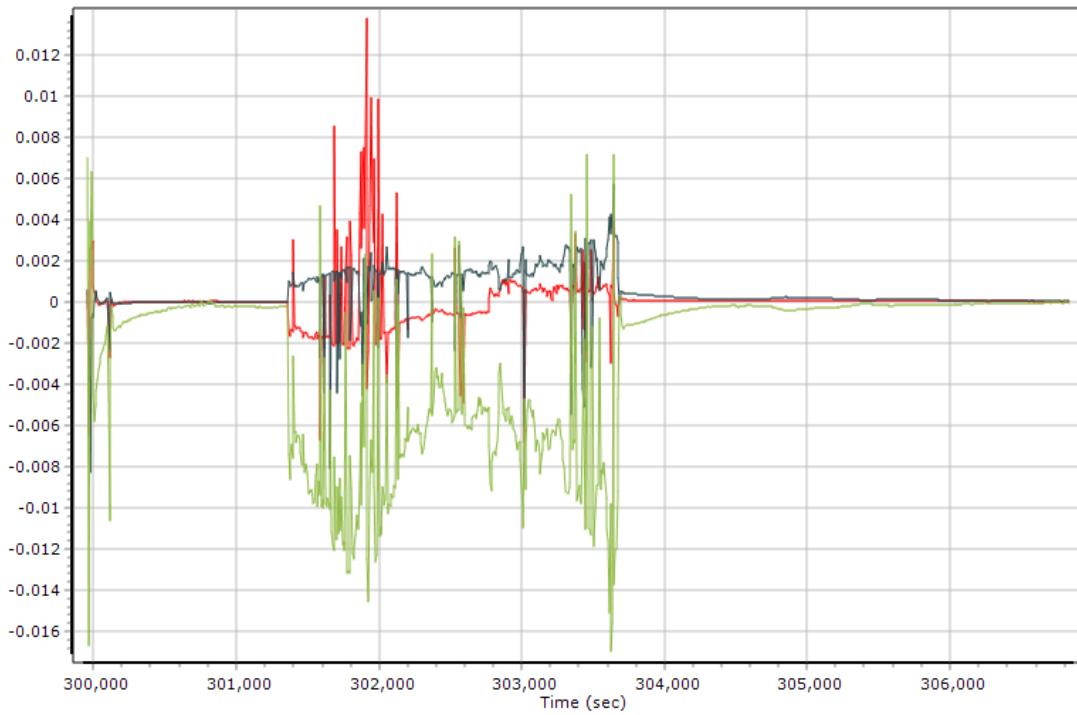
Timing

Start	<input type="text" value="299953.784"/>	Data	Incr. (sec)
End	<input type="text" value="306844.386"/>	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

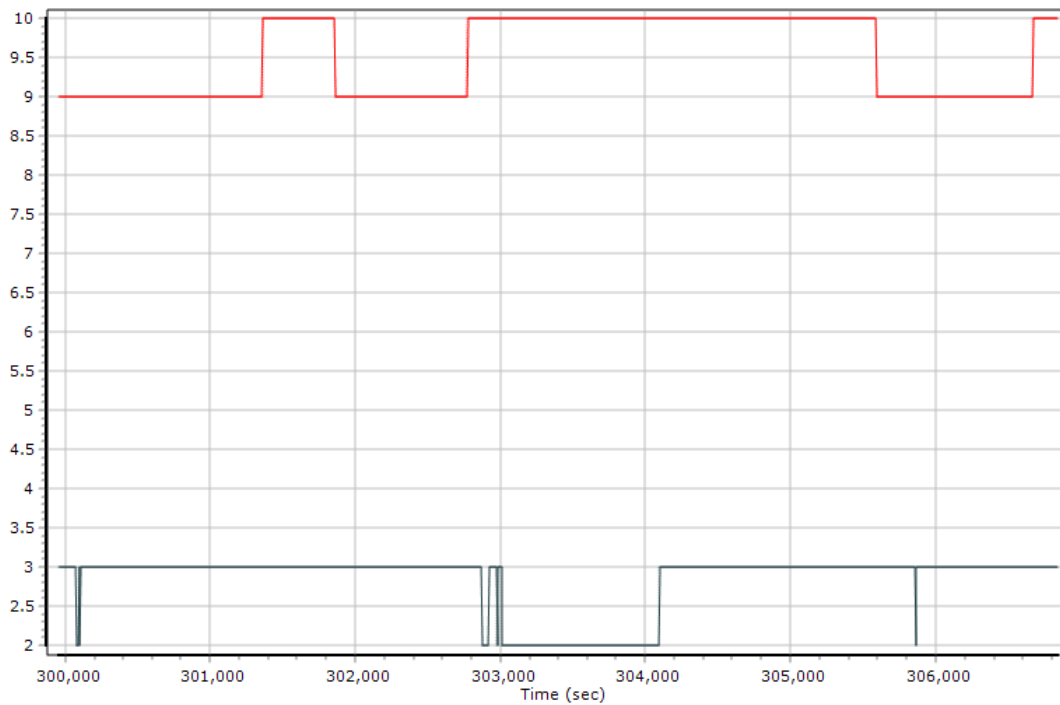
UTC Offset





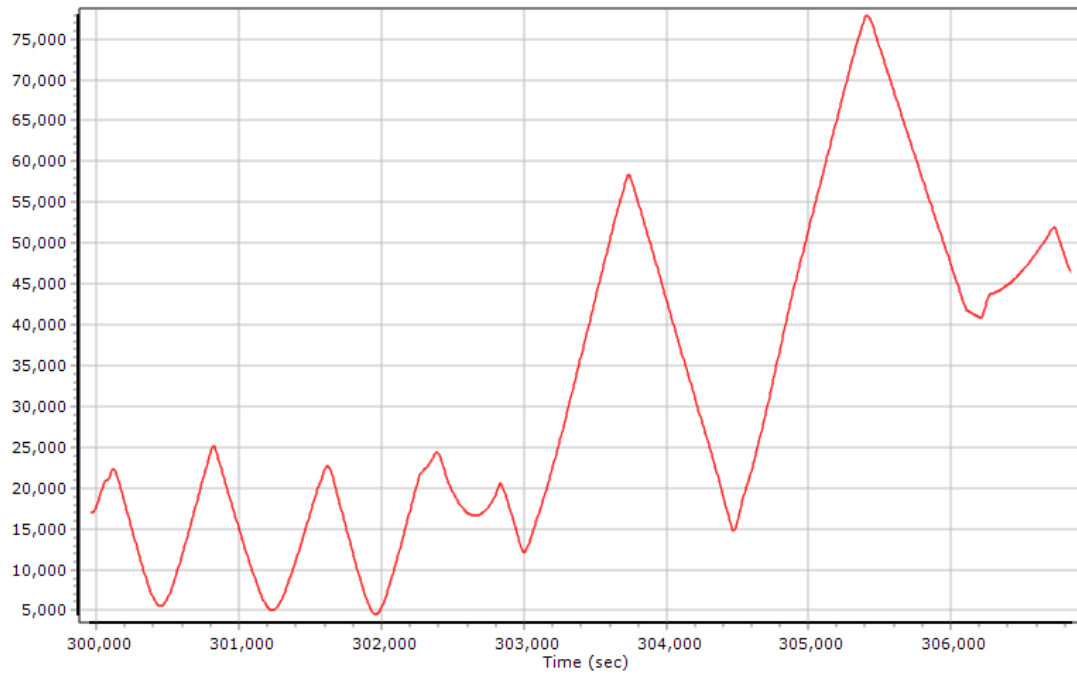


— North (m) — East (m) — Down (m) → DR mode



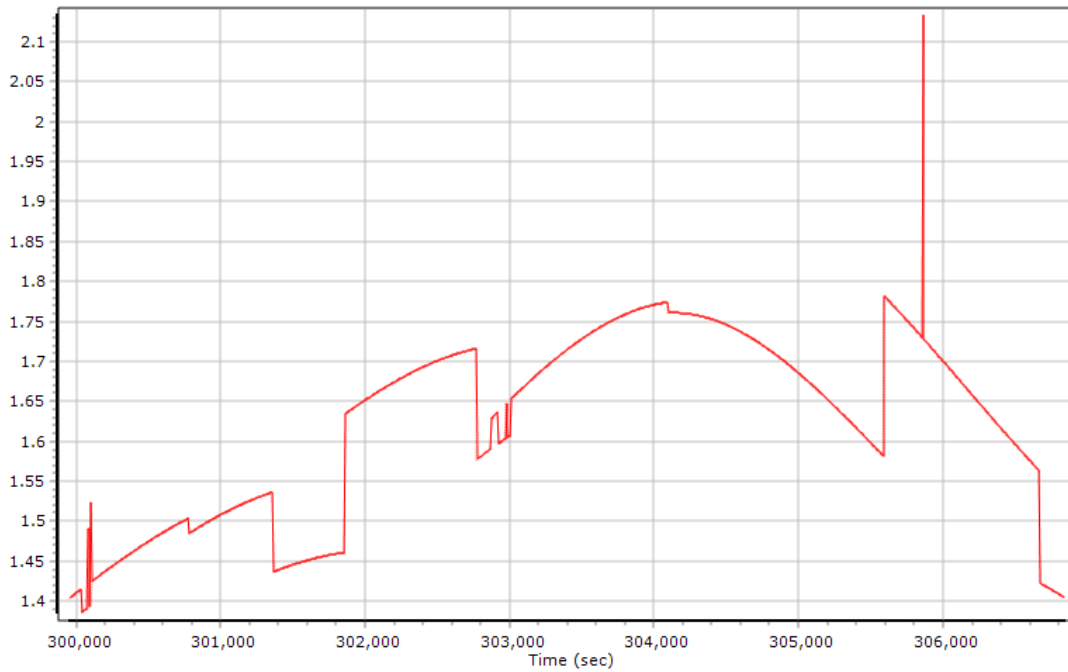
— Number of GPS Satellites — Number of GLONASS Satellites

Baseline Length (m)



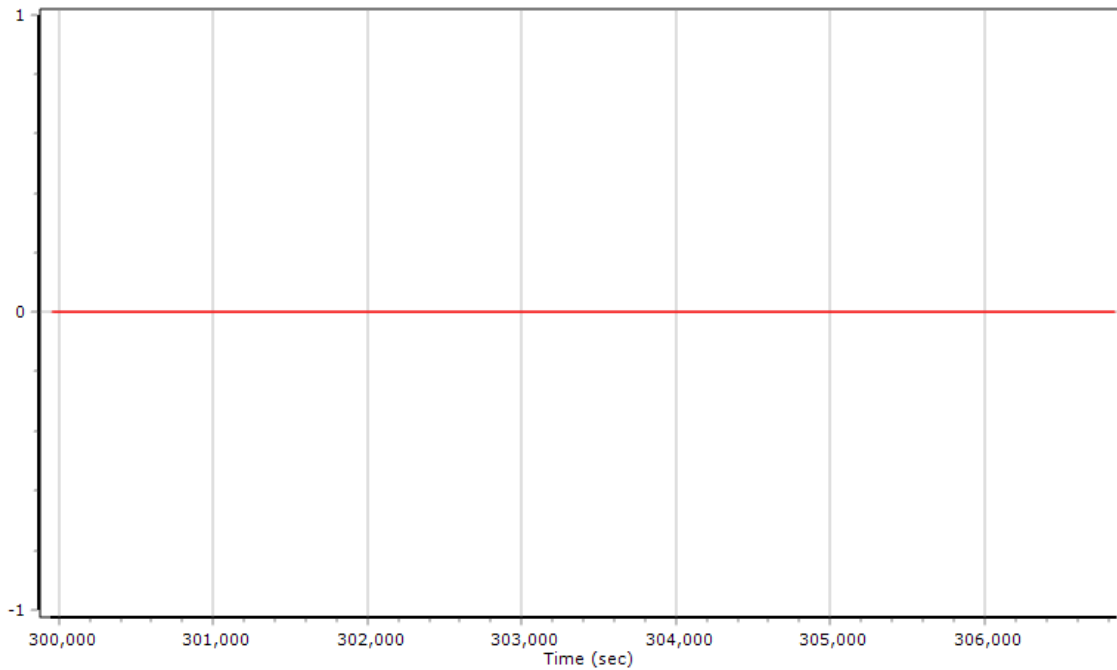
Forward Reverse

PDOP



Forward Reverse

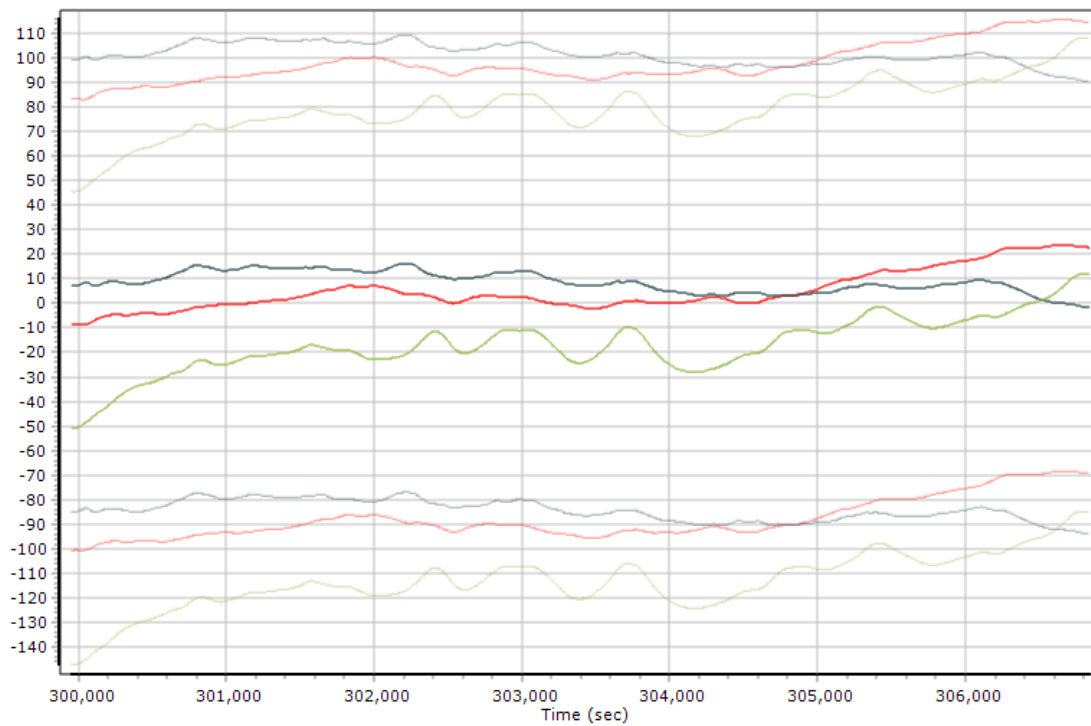
Processing mode



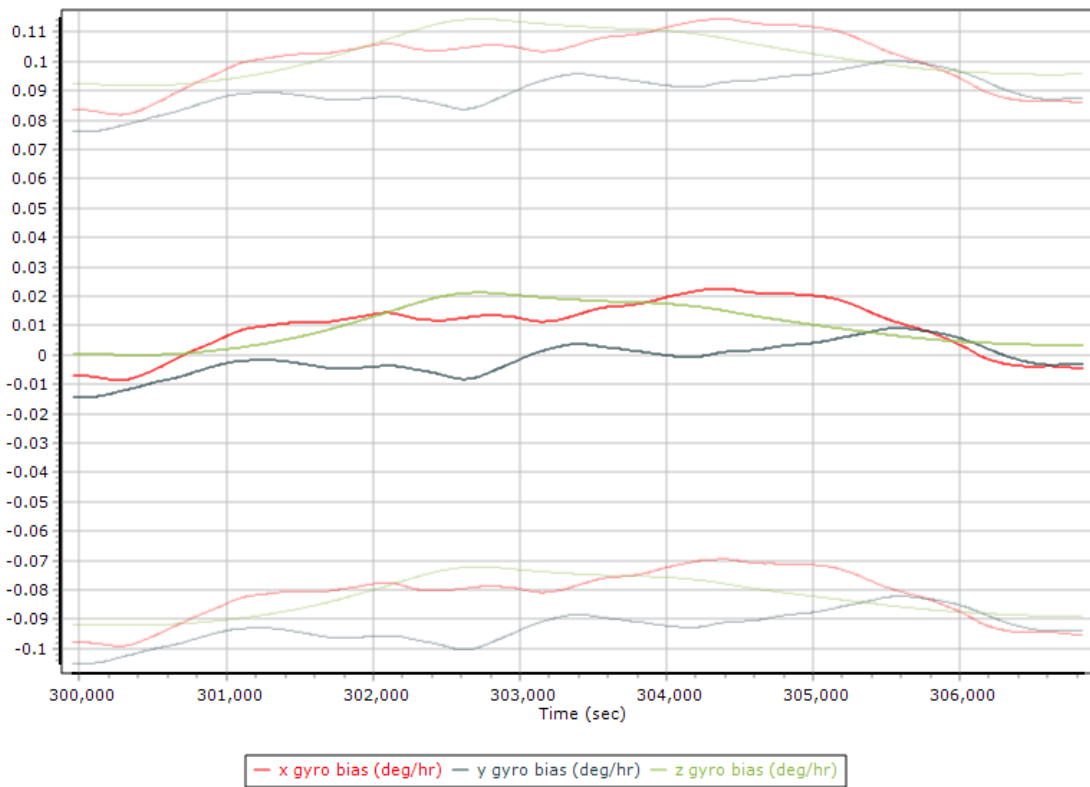
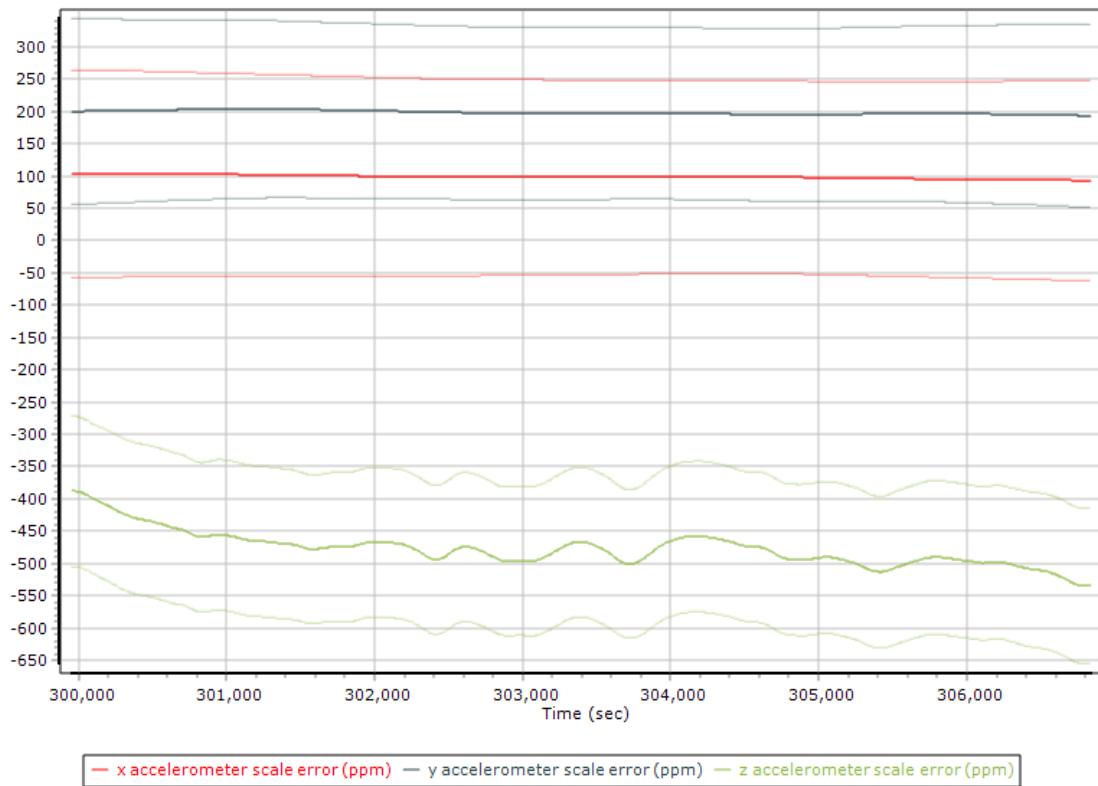
Forward Reverse

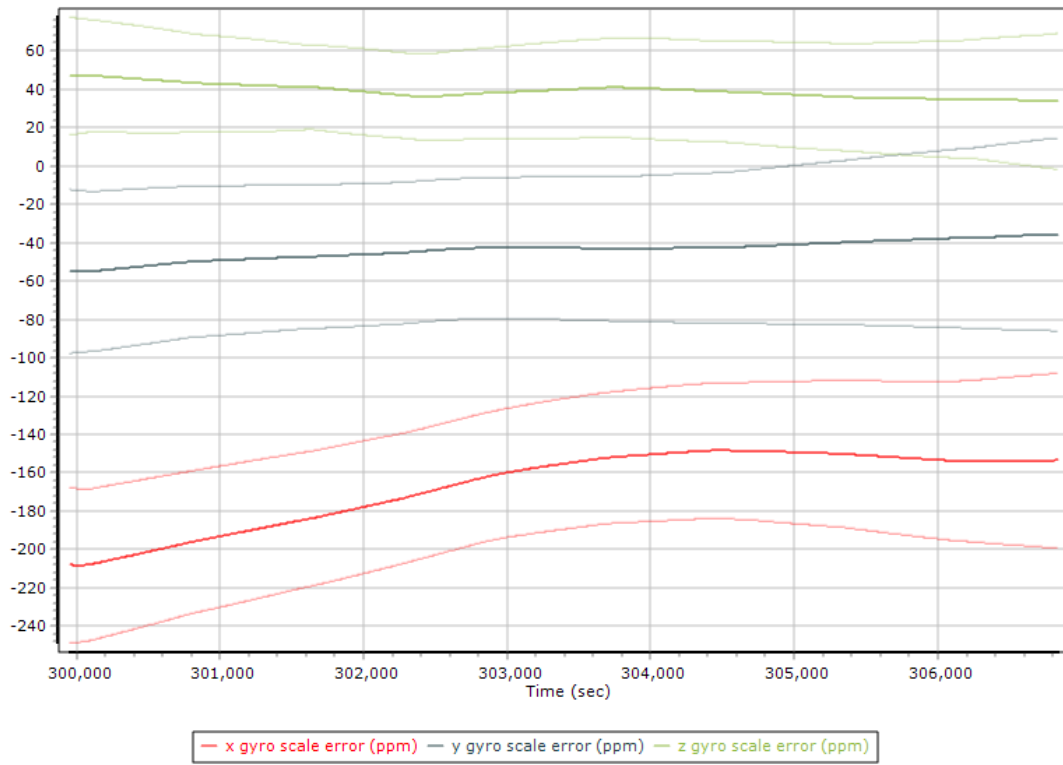
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

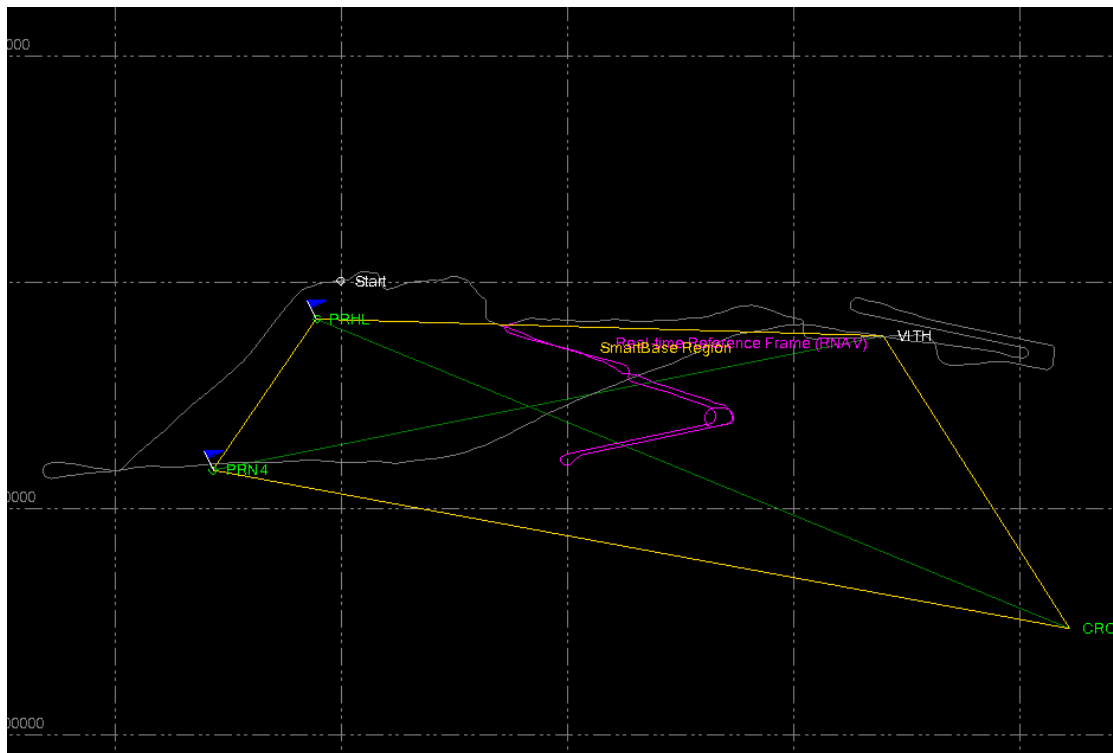


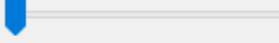
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)





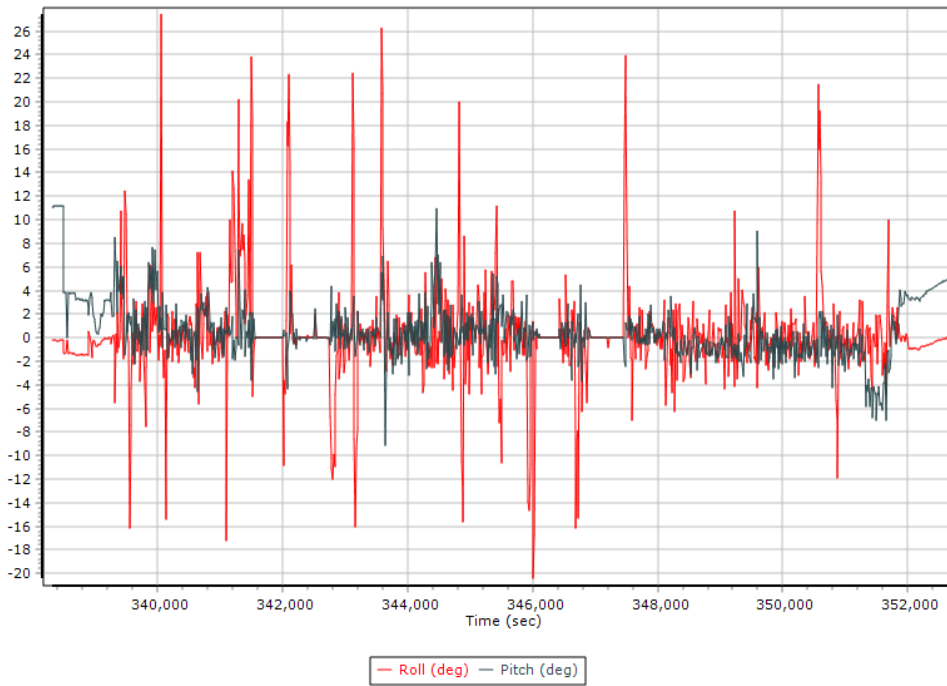
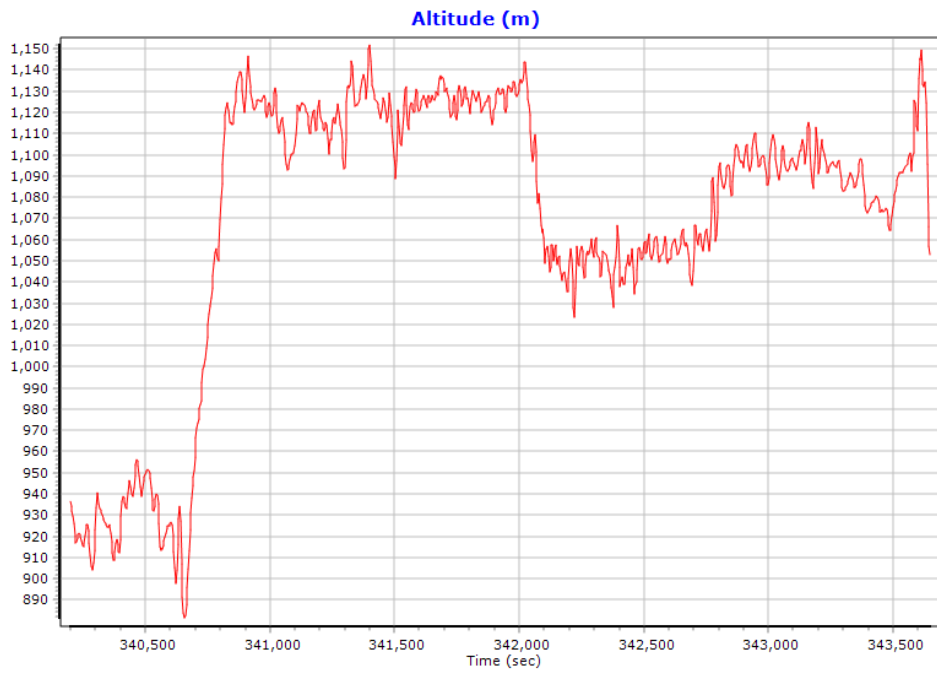
AZT18157B

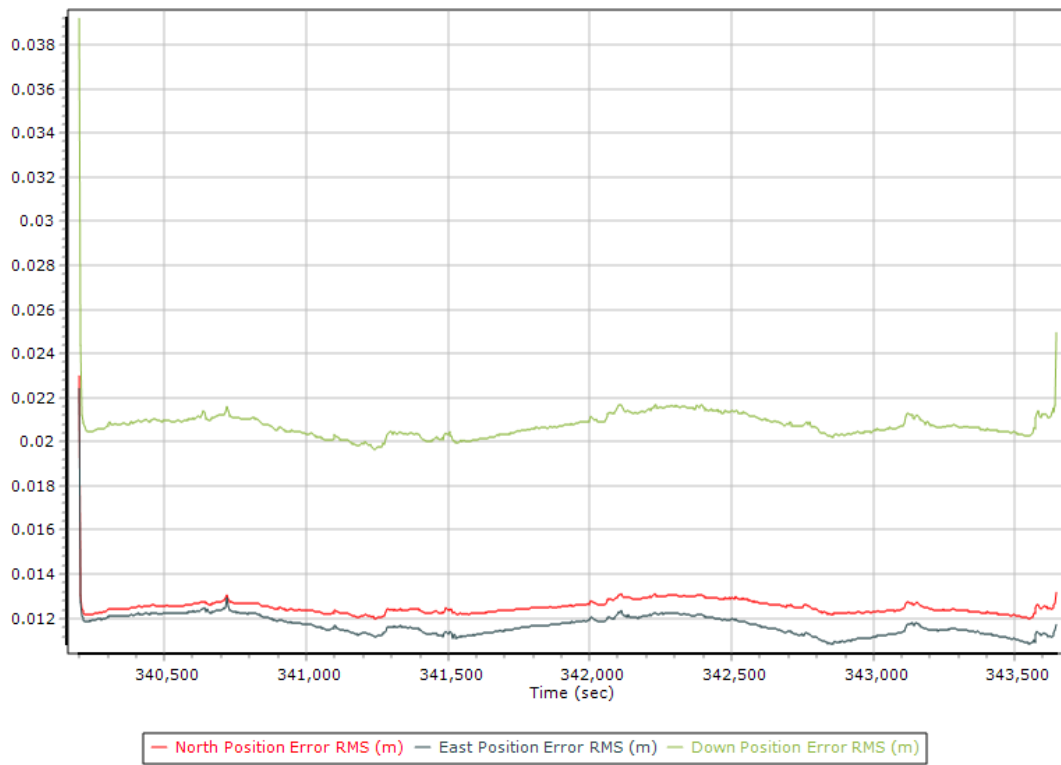


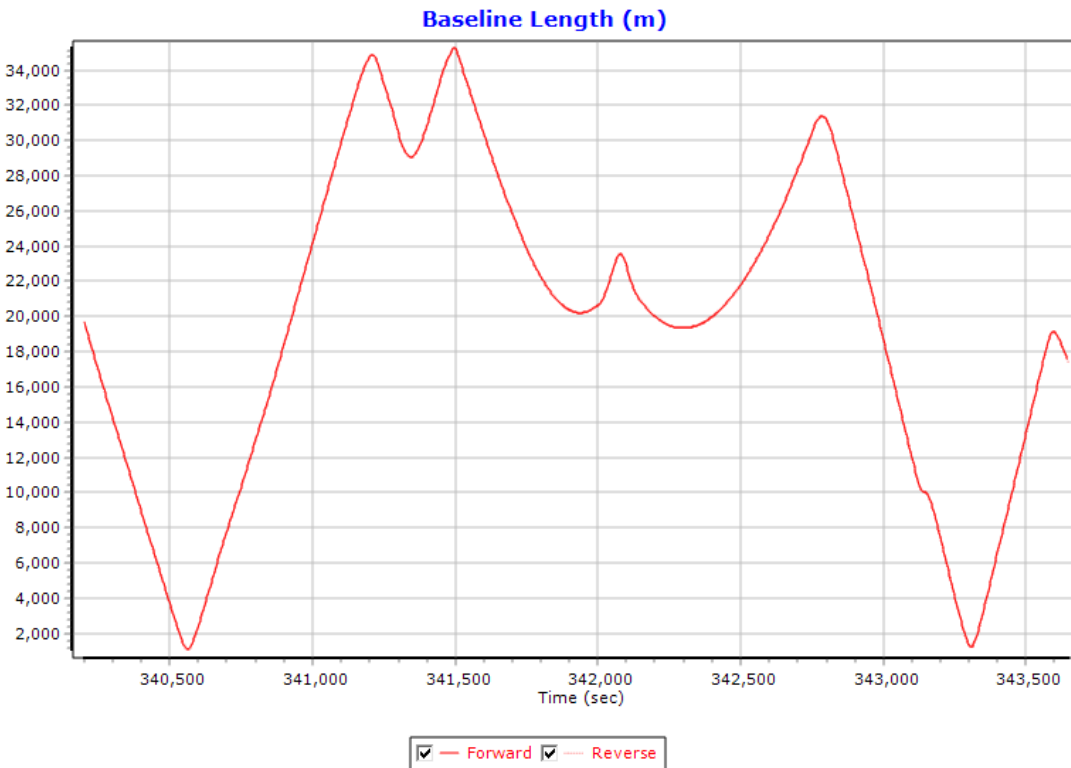
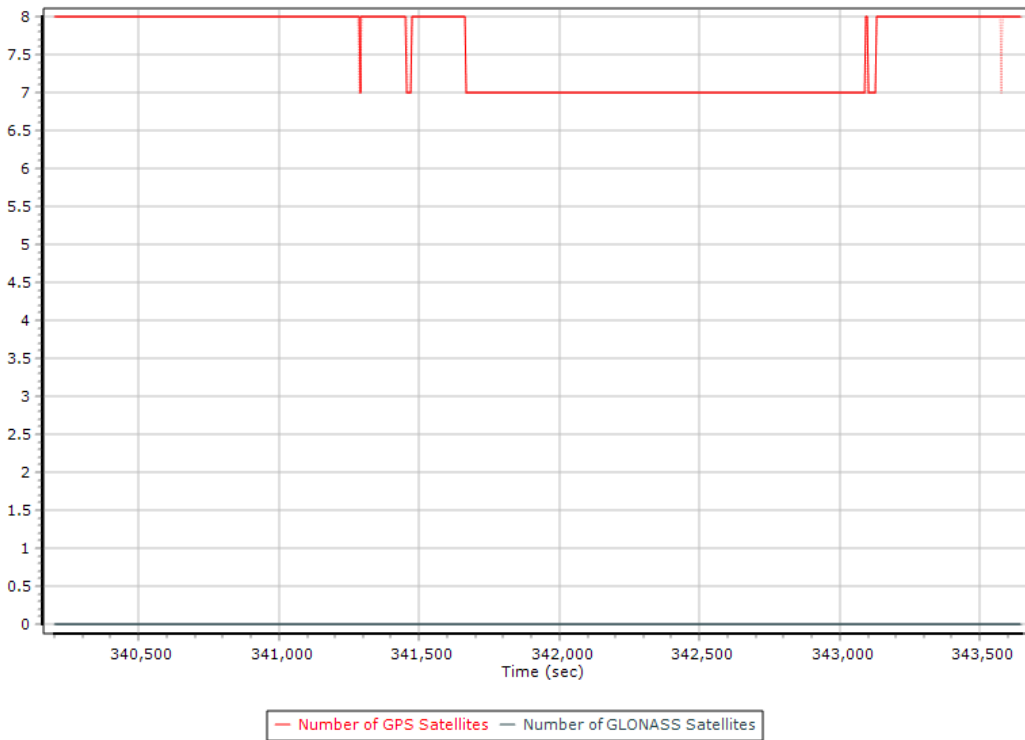
Stabilized Mount to IMU Lever Arm X <input type="text" value="-0.034 m"/> Y <input type="text" value="-0.010 m"/> Z <input type="text" value="-0.352 m"/>		Stabilized Mount to IMU Mounting Angles X <input type="text" value="0.000 deg"/> Y <input type="text" value="0.000 deg"/> Z <input type="text" value="0.000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

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

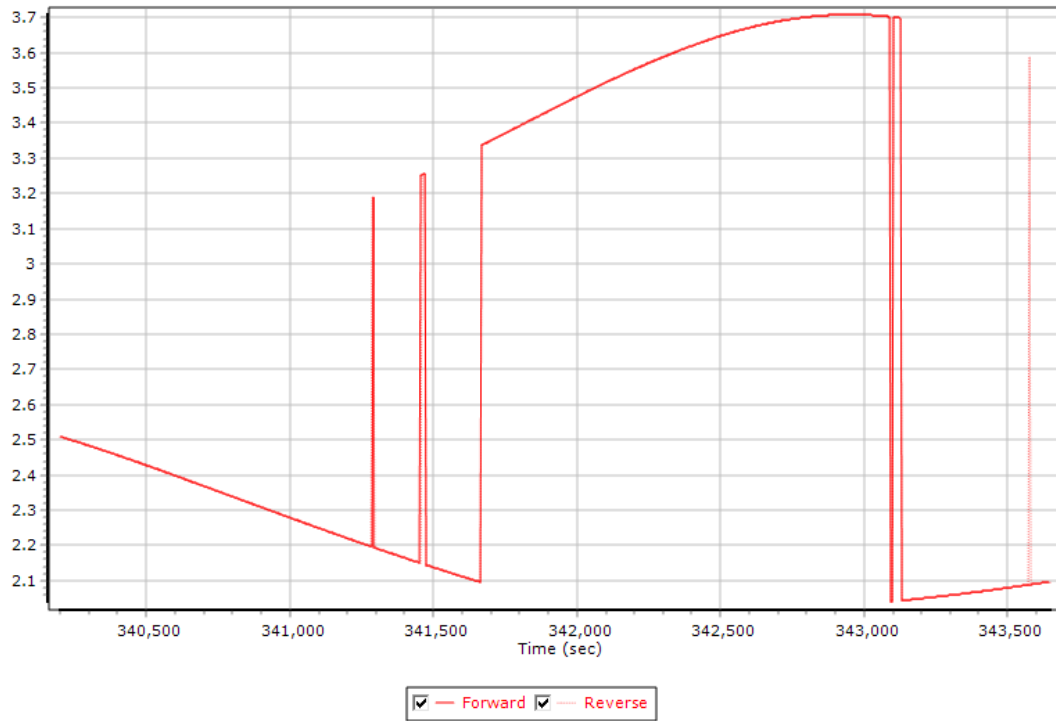
Timing Start <input type="text" value="340197.813"/> End <input type="text" value="343650.620"/> <input type="checkbox"/> Entire time interval <input checked="" type="checkbox"/> Seconds of start week UTC Offset <input type="text" value="18.000"/>		<table border="1"> <thead> <tr> <th>Data</th> <th>Incr. (sec)</th> </tr> </thead> <tbody> <tr> <td>Output Record</td> <td>0.005000</td> </tr> <tr> <td>IMU</td> <td>0.005000</td> </tr> <tr> <td>Primary GNSS</td> <td>1.000000</td> </tr> </tbody> </table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000
Data	Incr. (sec)									
Output Record	0.005000									
IMU	0.005000									
Primary GNSS	1.000000									



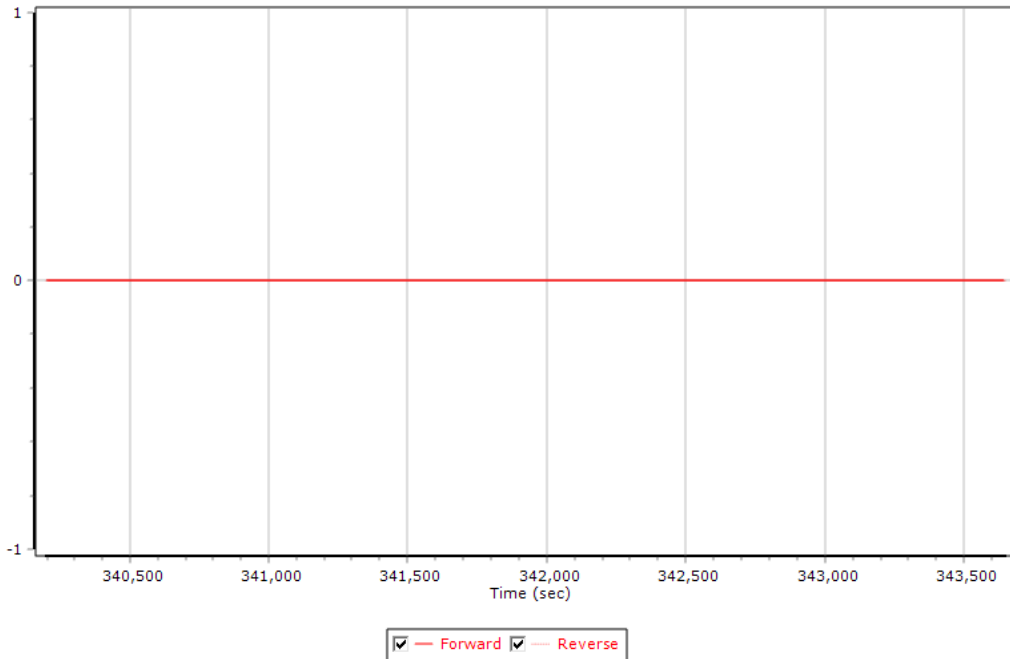




PDOP

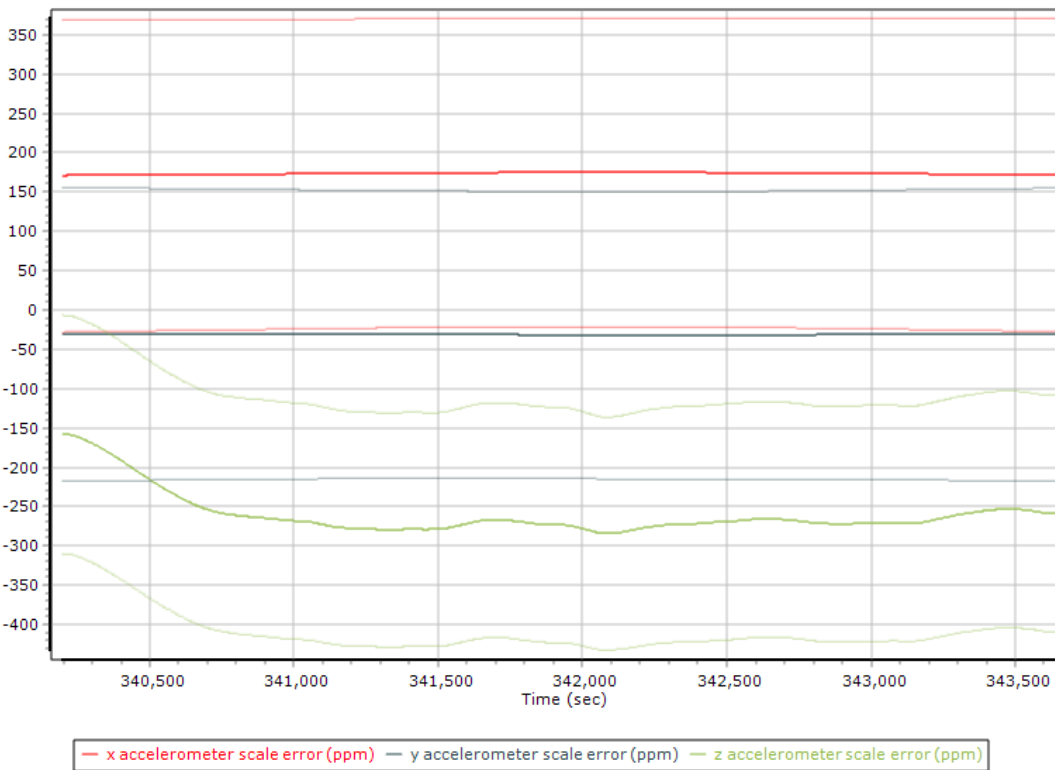
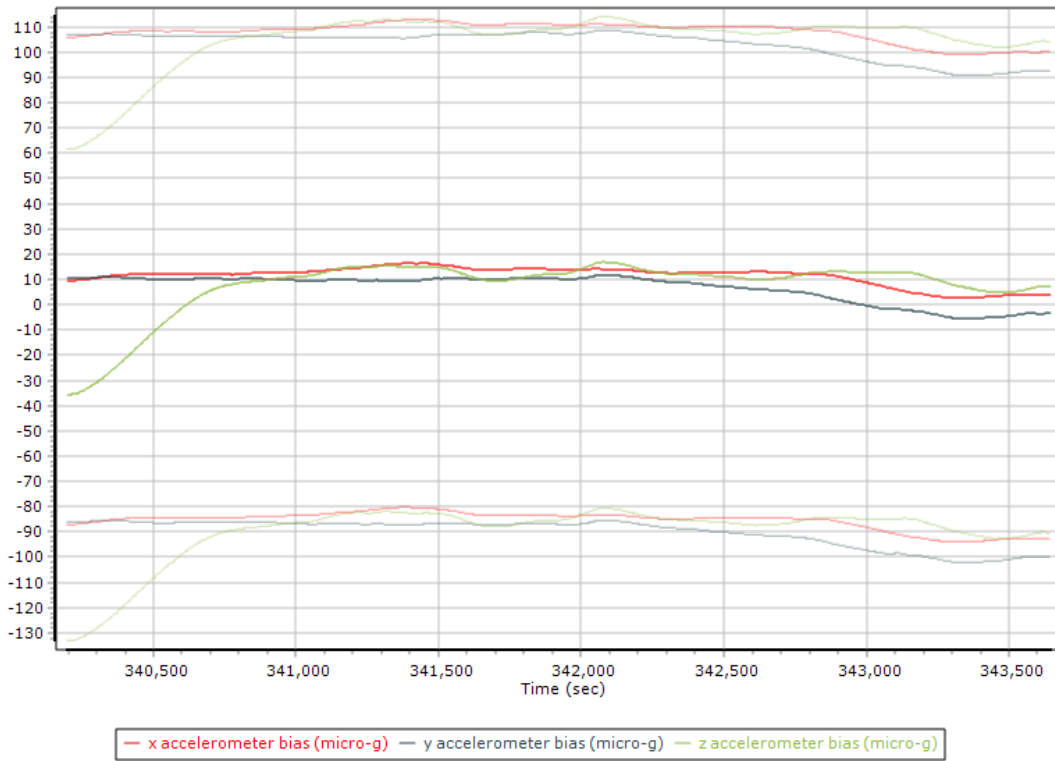


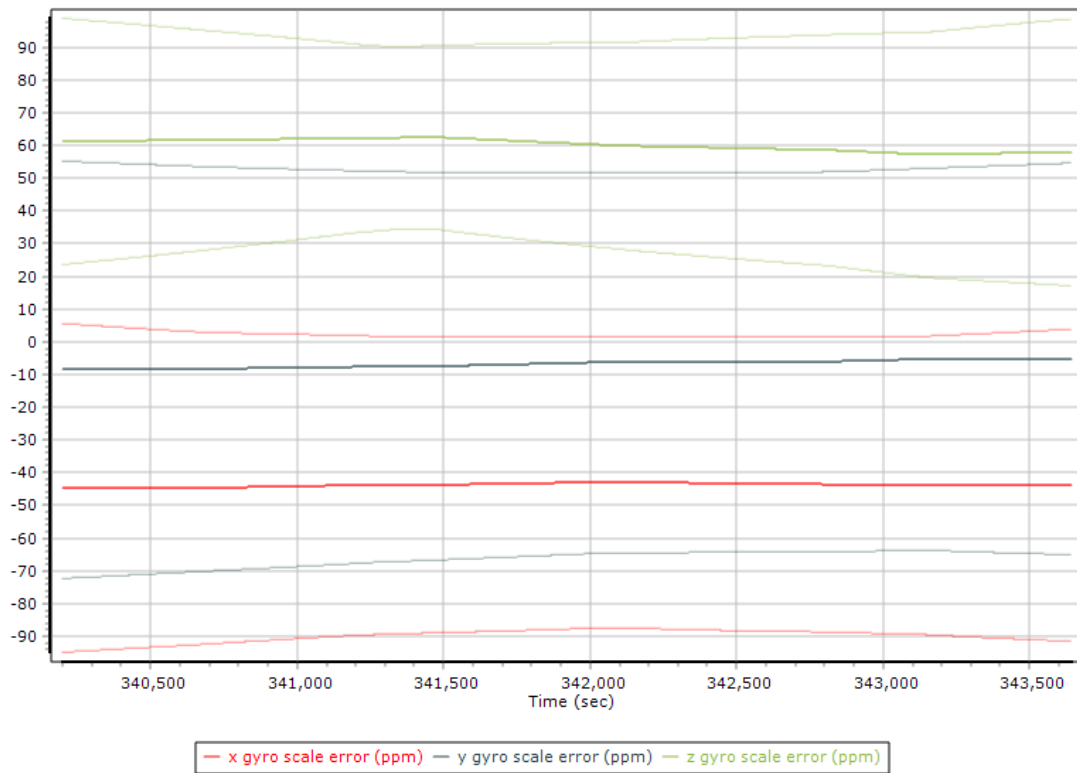
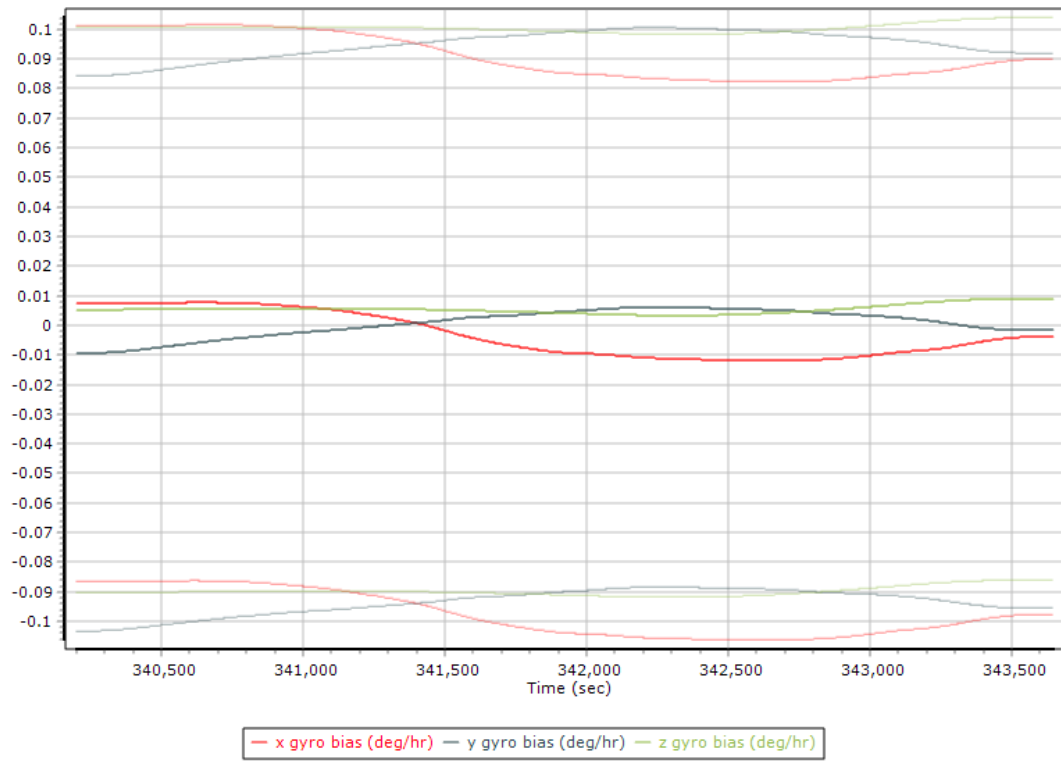
Processing mode



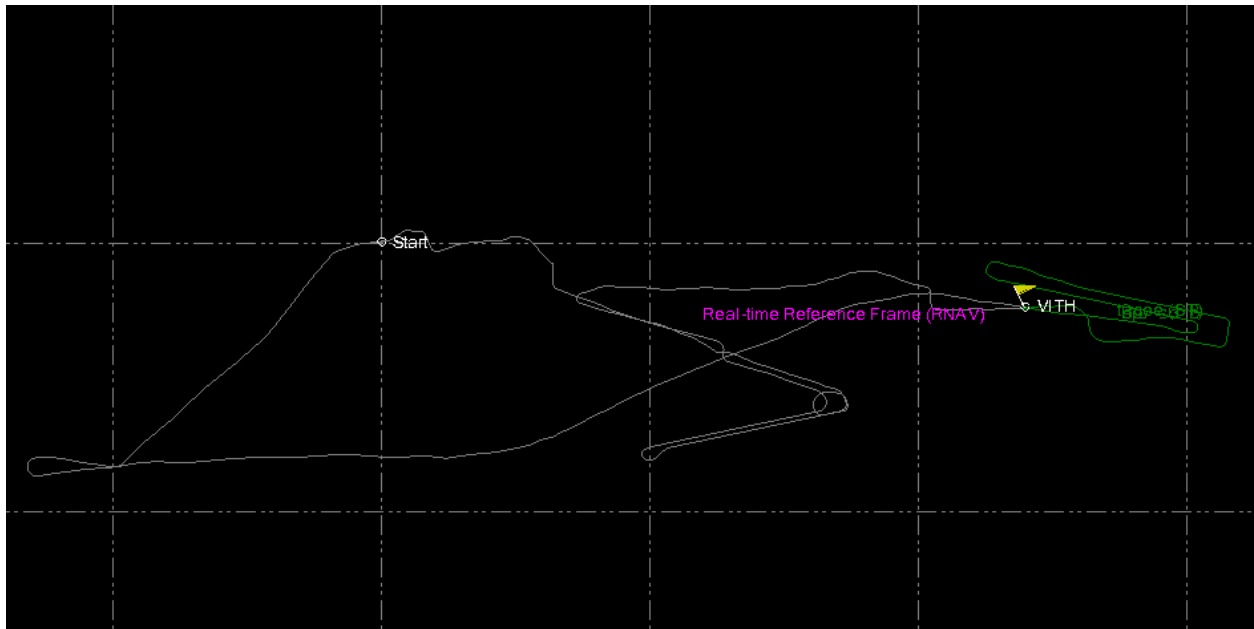
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

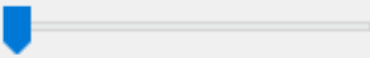
Sensor Errors





AZT18157B2



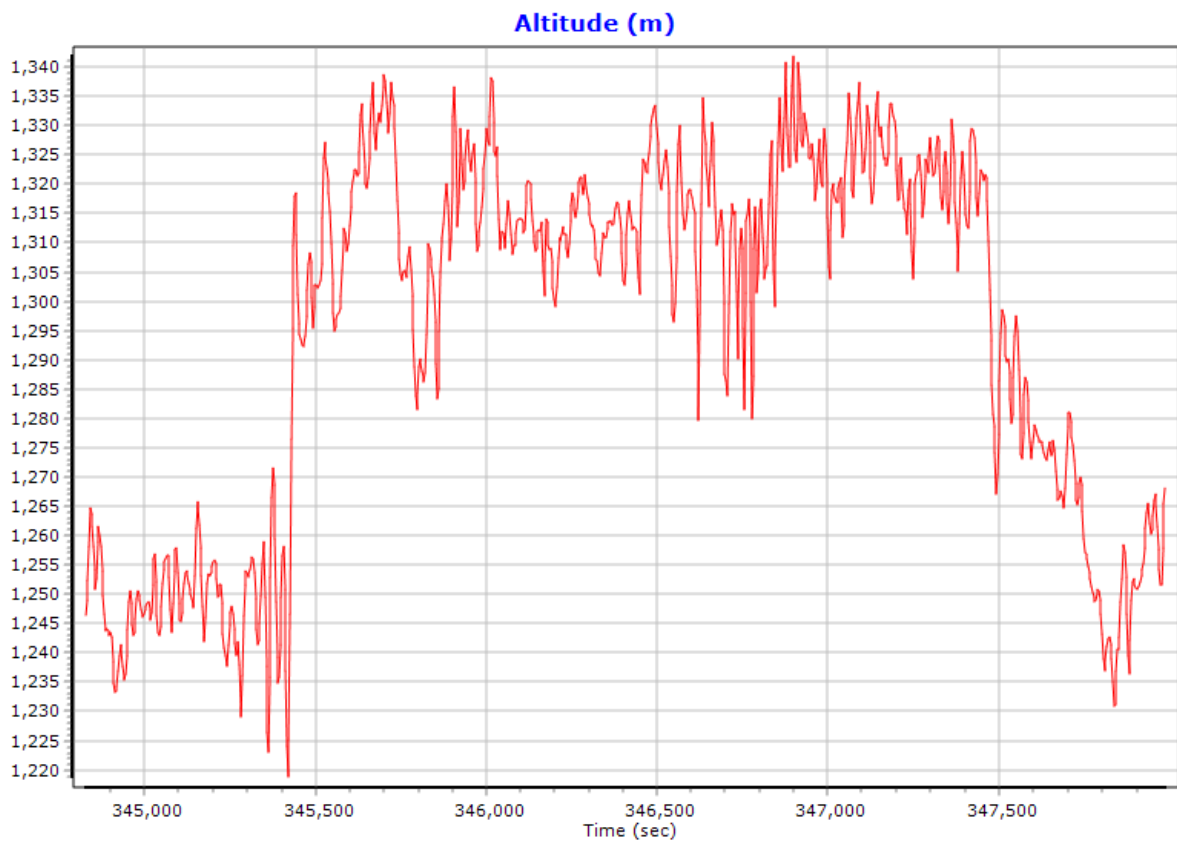
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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 			
<3cm 10cm 50cm 1m 10m			

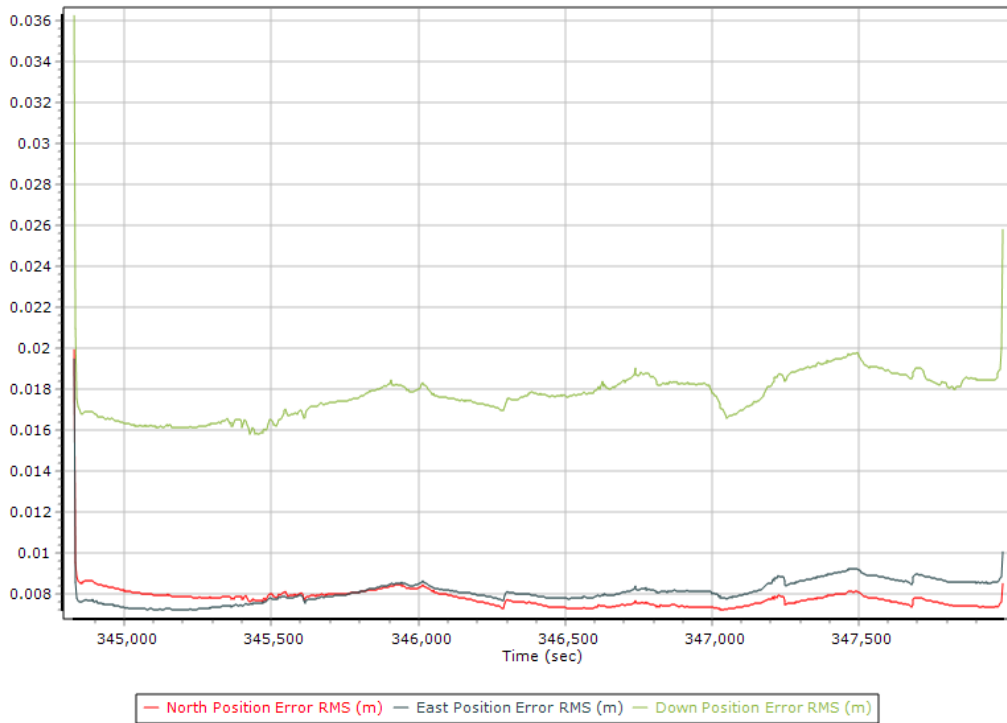
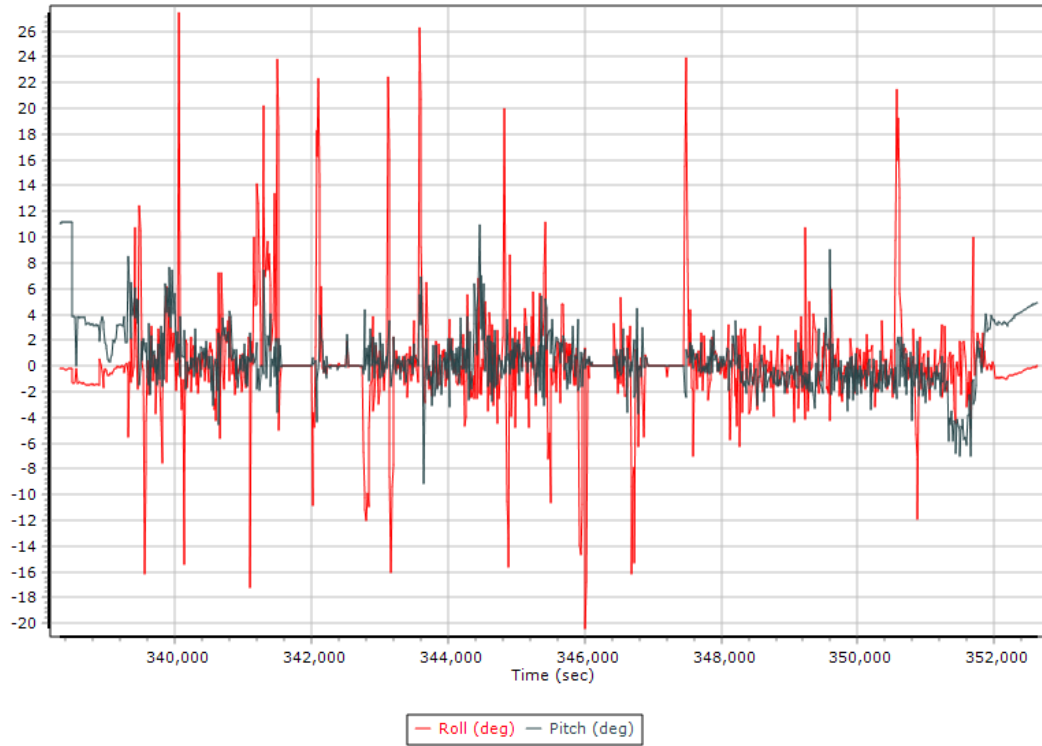
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

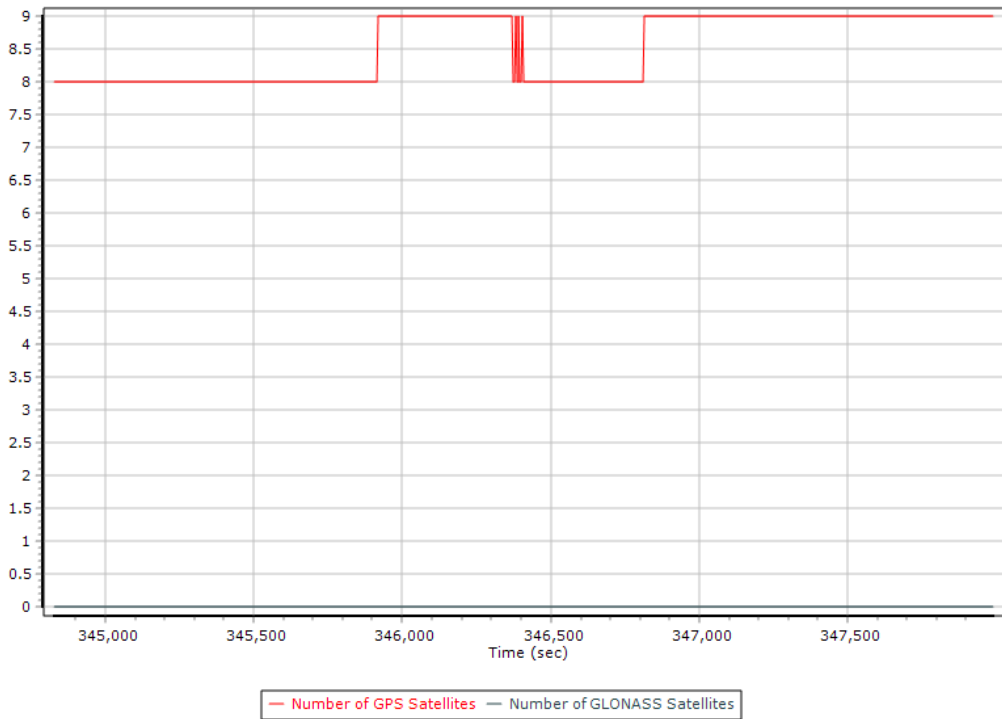
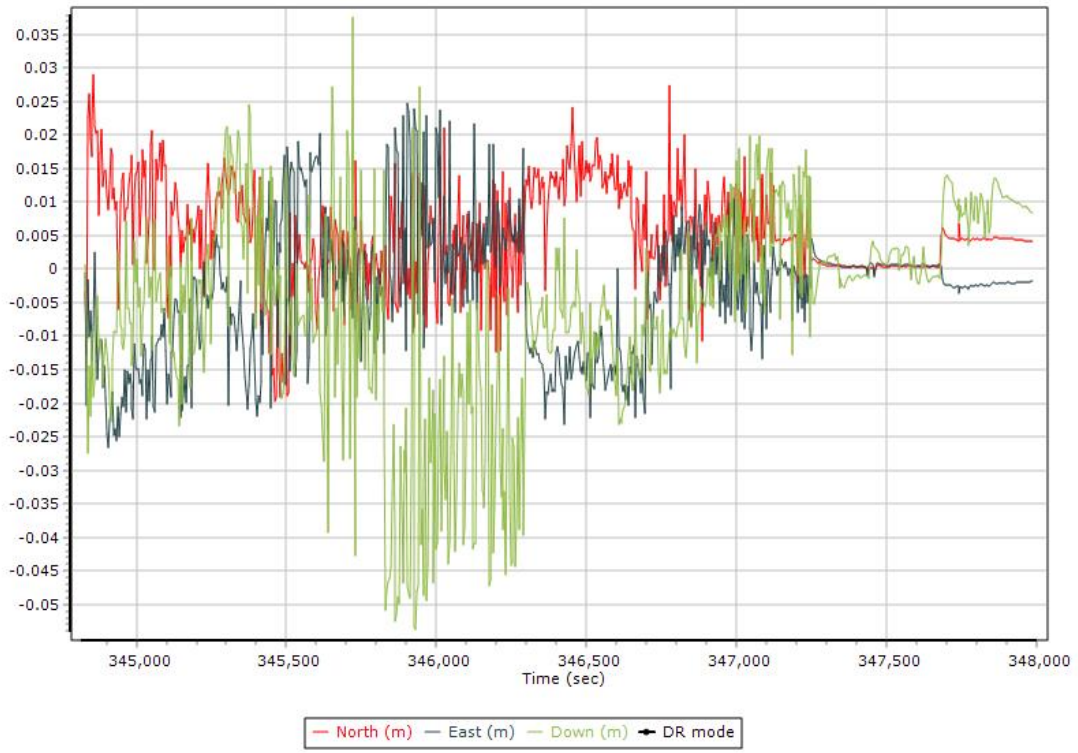
Timing

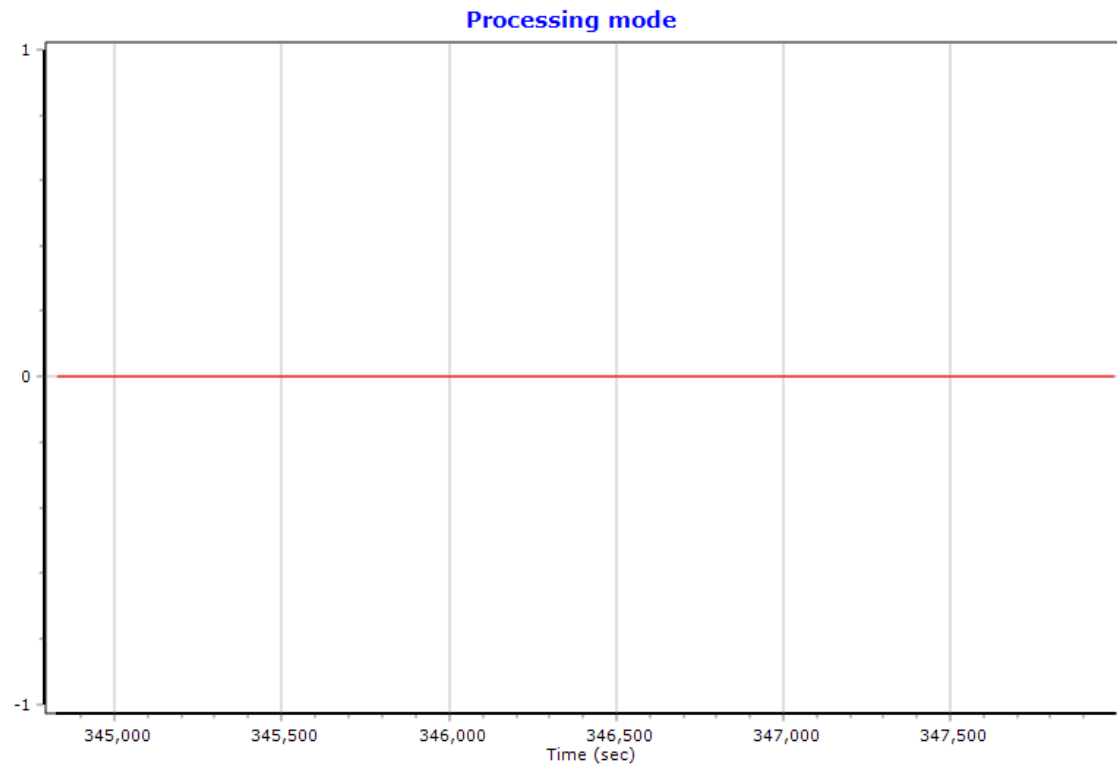
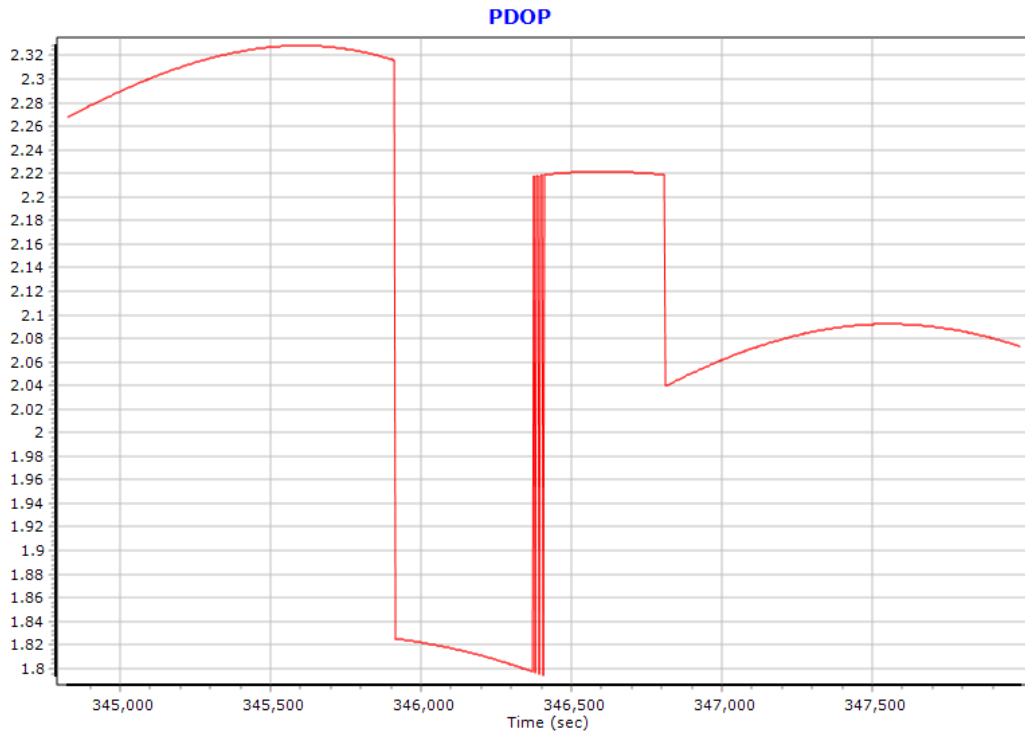
Start	345186.980	Data	Incr. (sec)
End	347989.636	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset

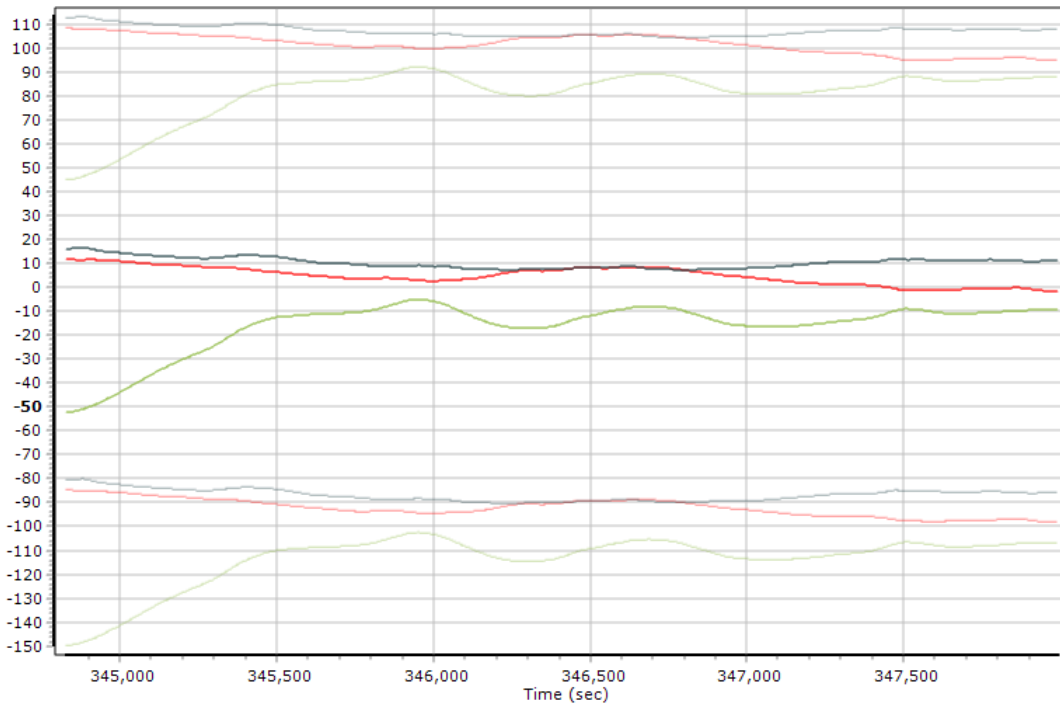




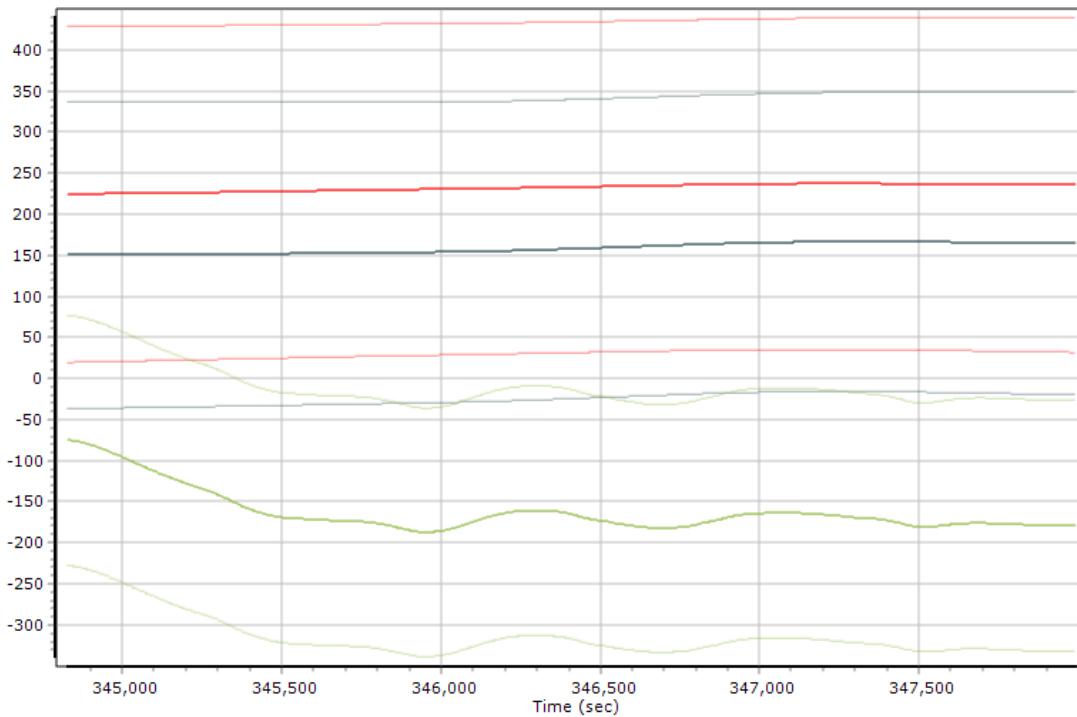




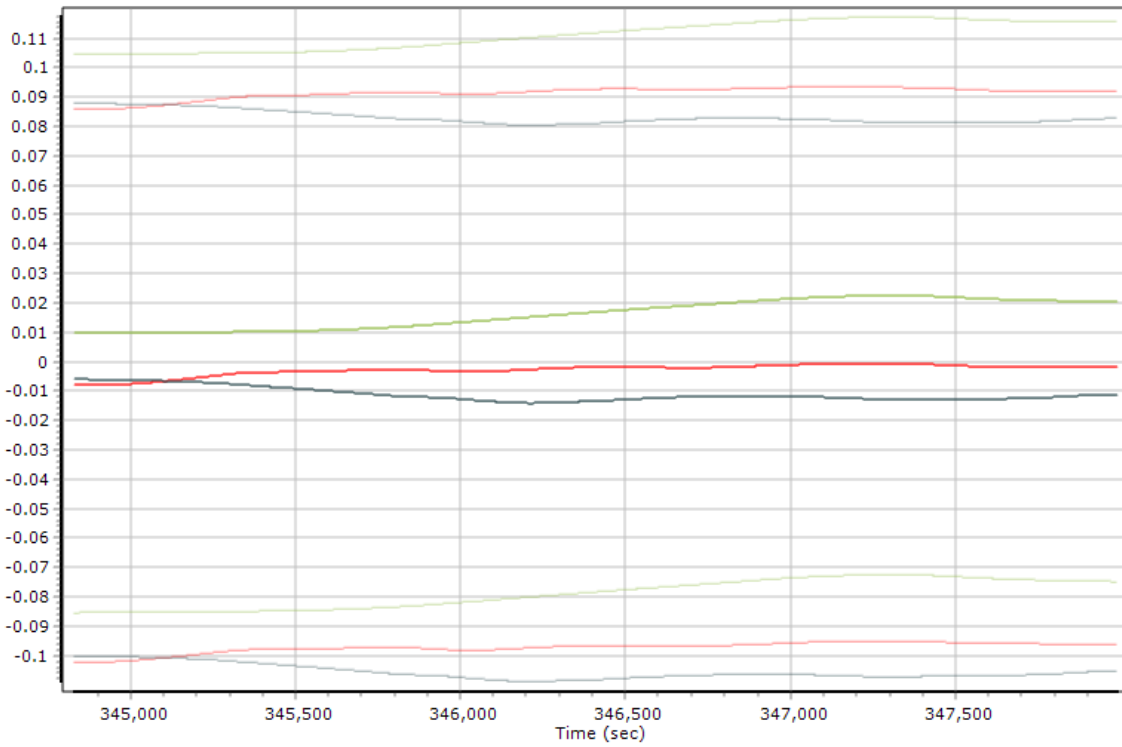
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



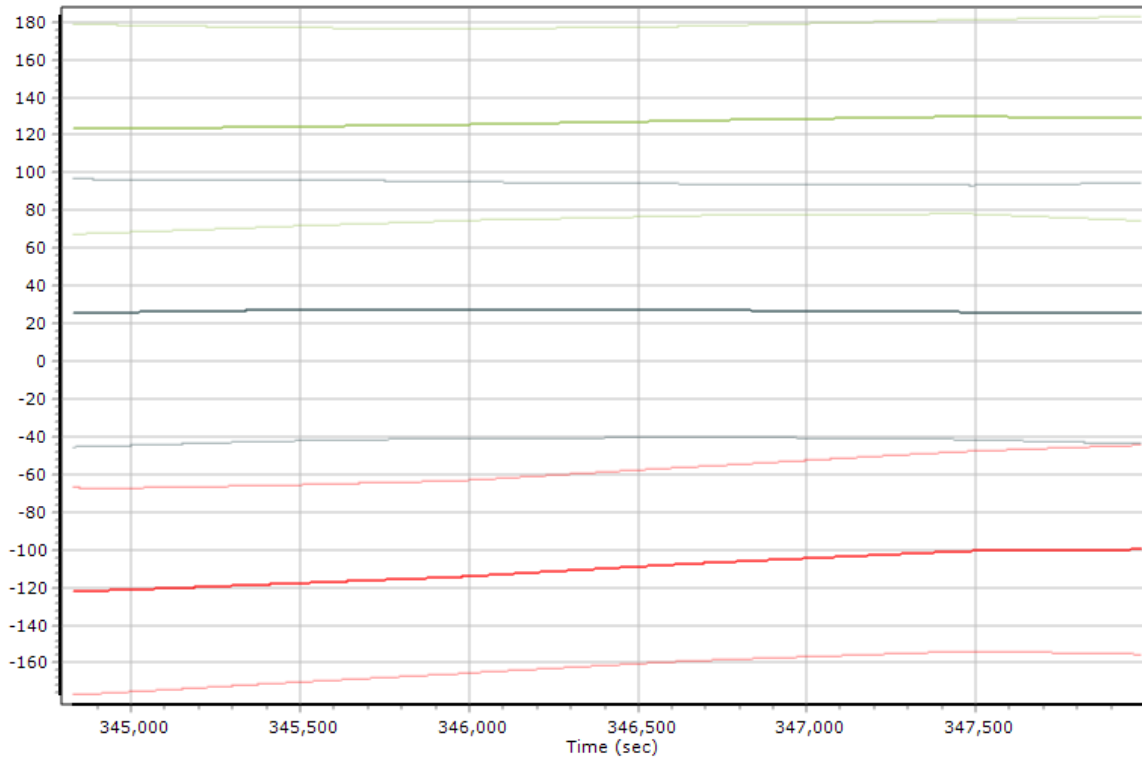
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)



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

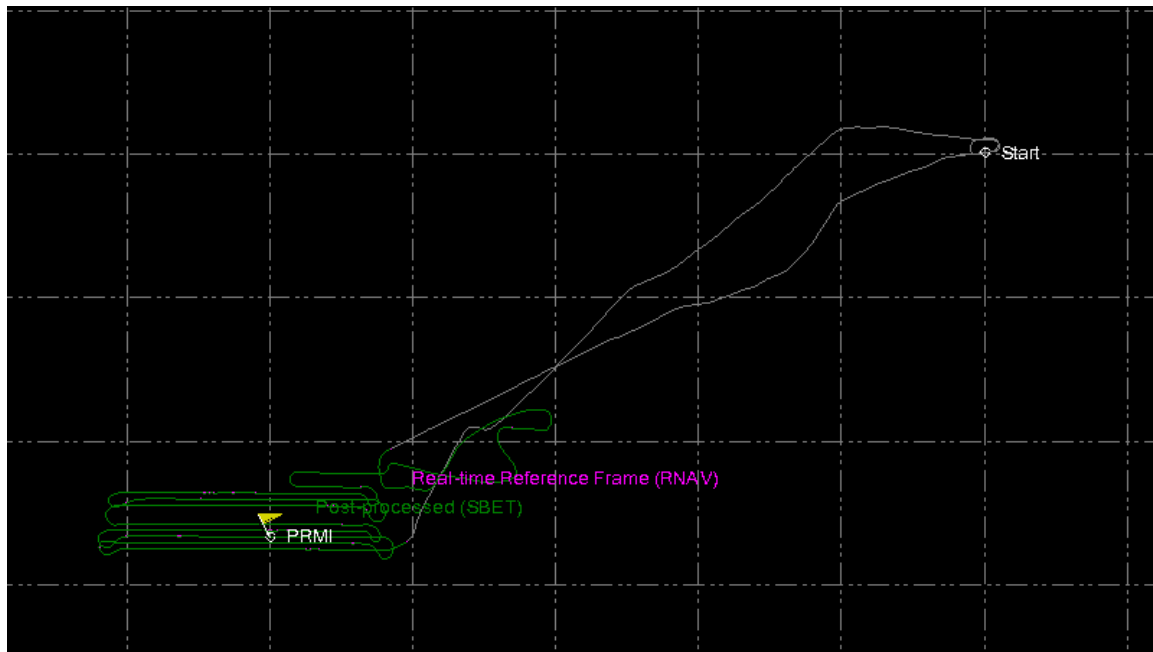


x gyro bias (deg/hr) y gyro bias (deg/hr) z gyro bias (deg/hr)



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

AZT18158A



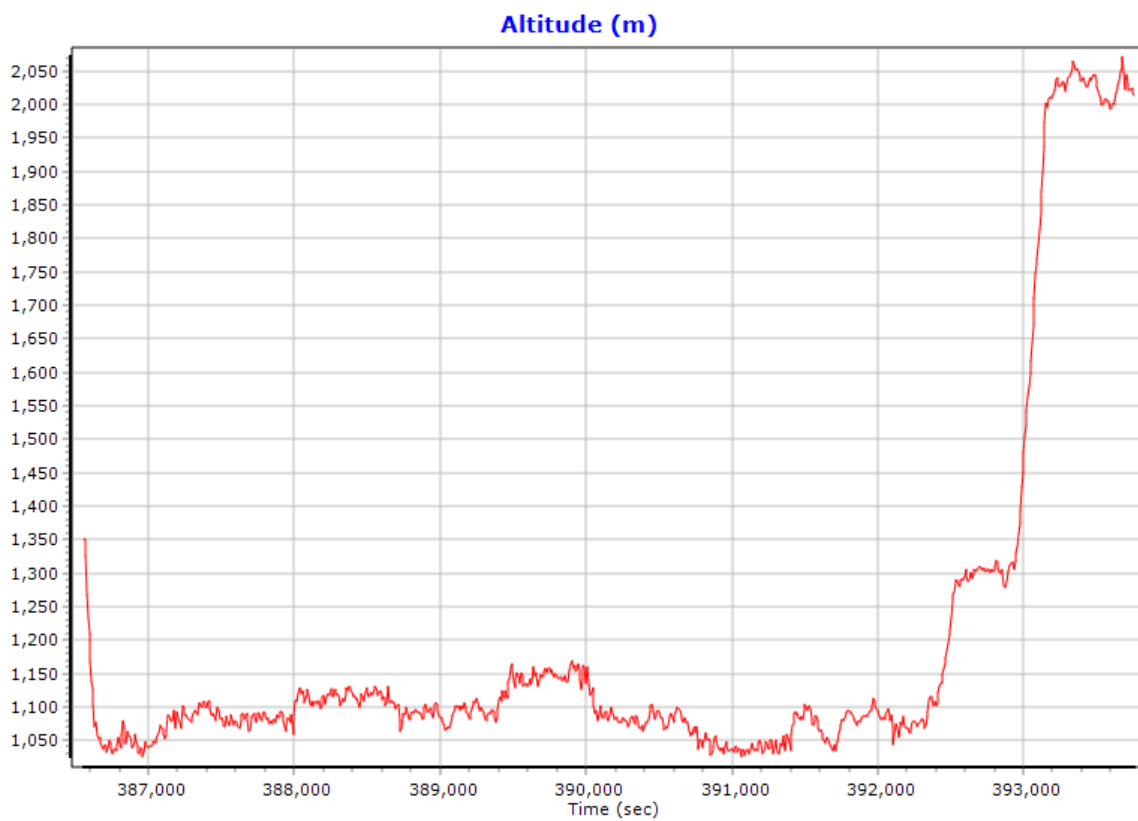
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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"/>		
	<p><3cm 10cm 50cm 1m 10m</p>		

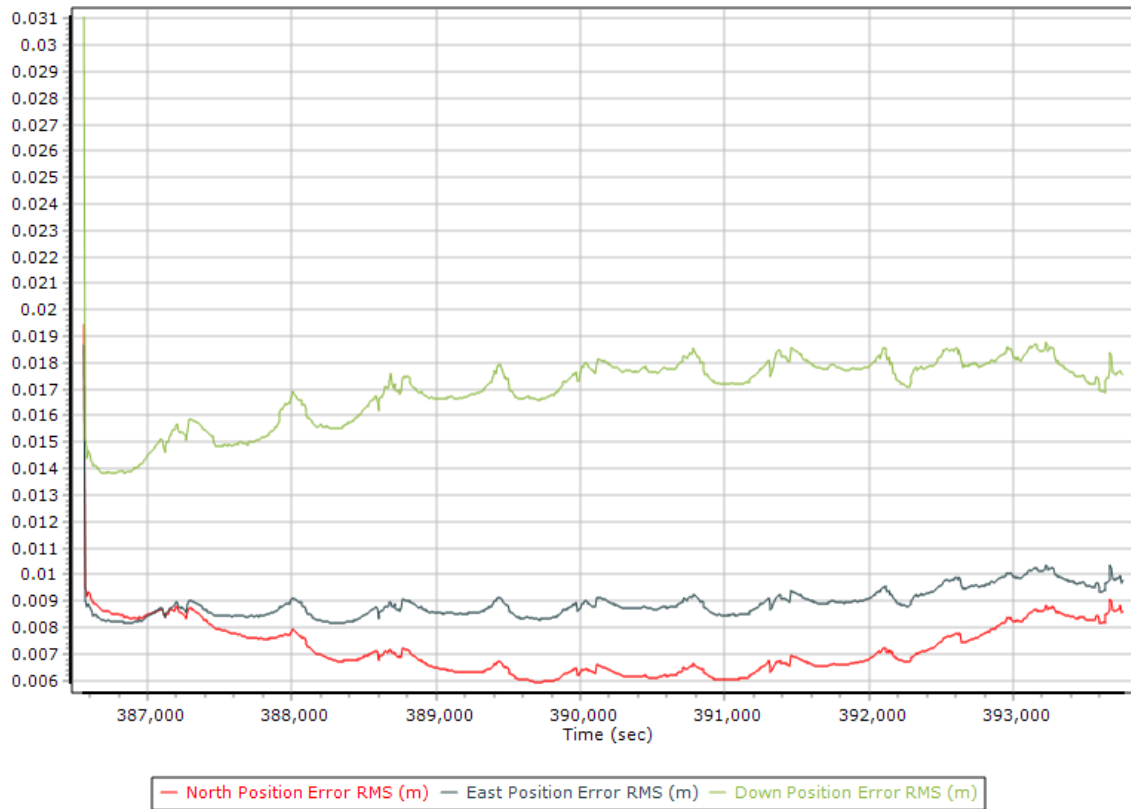
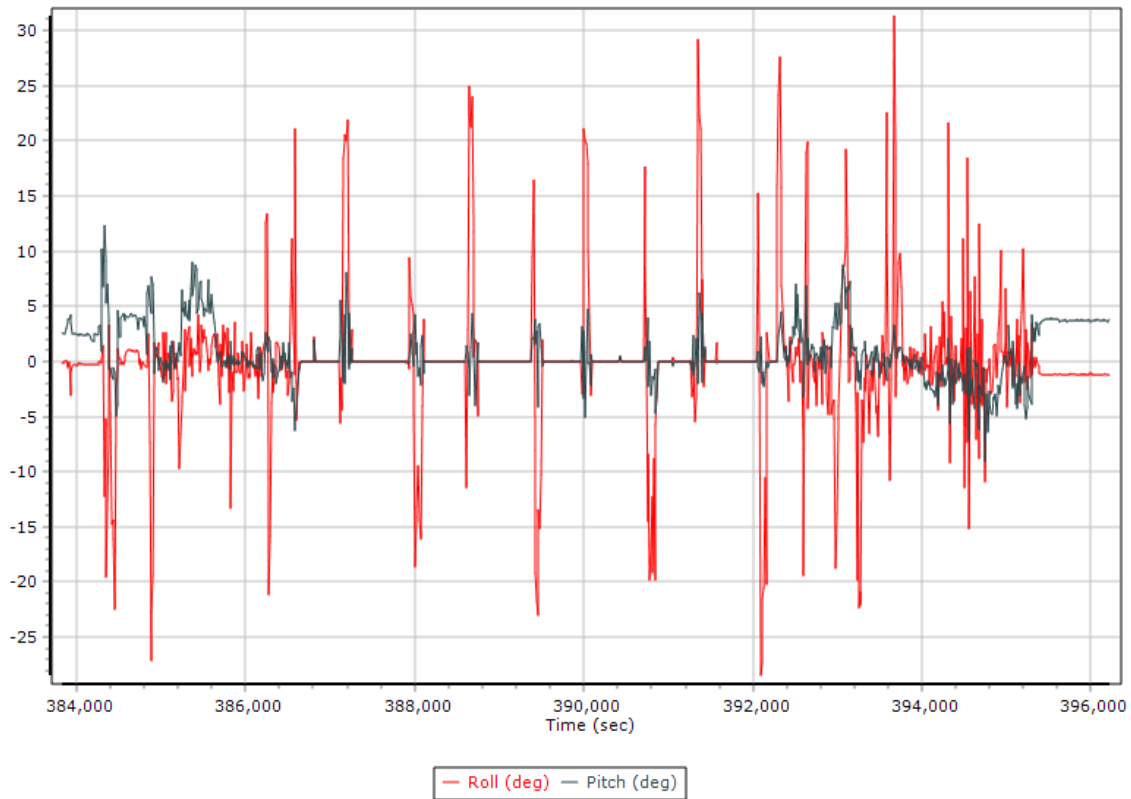
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

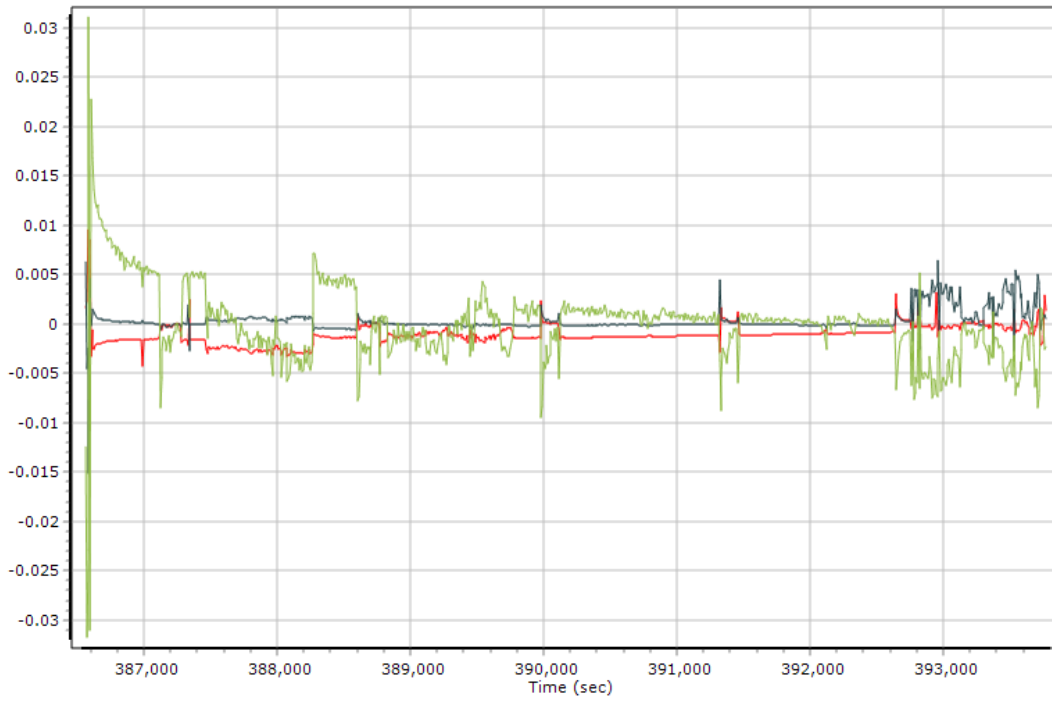
Timing

Start	386556.000	Data	Incr. (sec)
End	393769.000	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

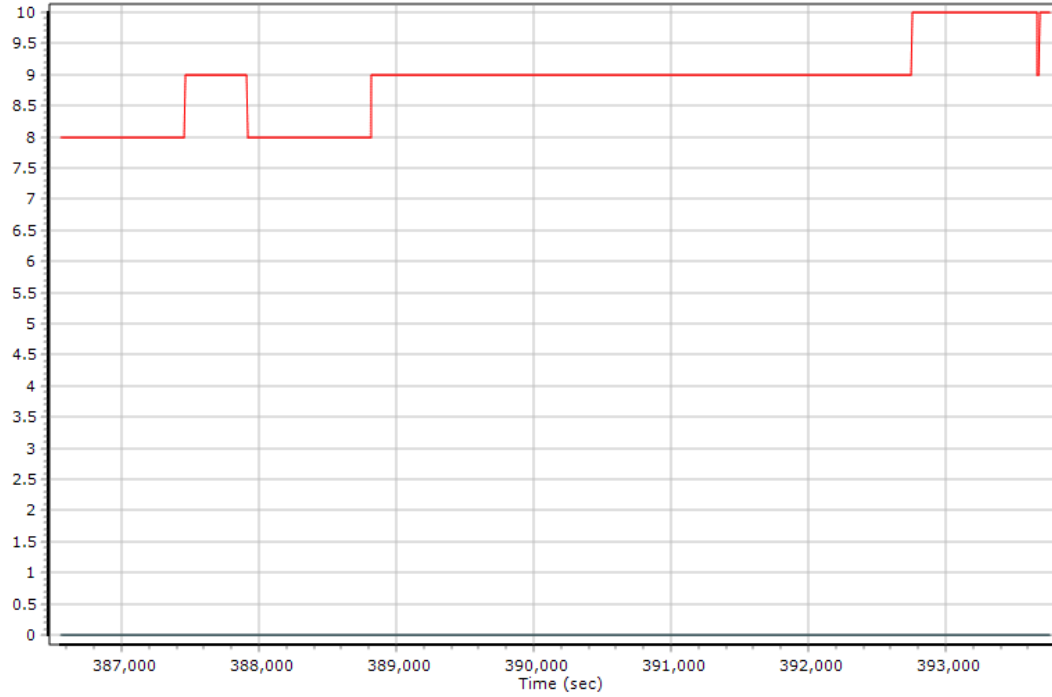
UTC Offset





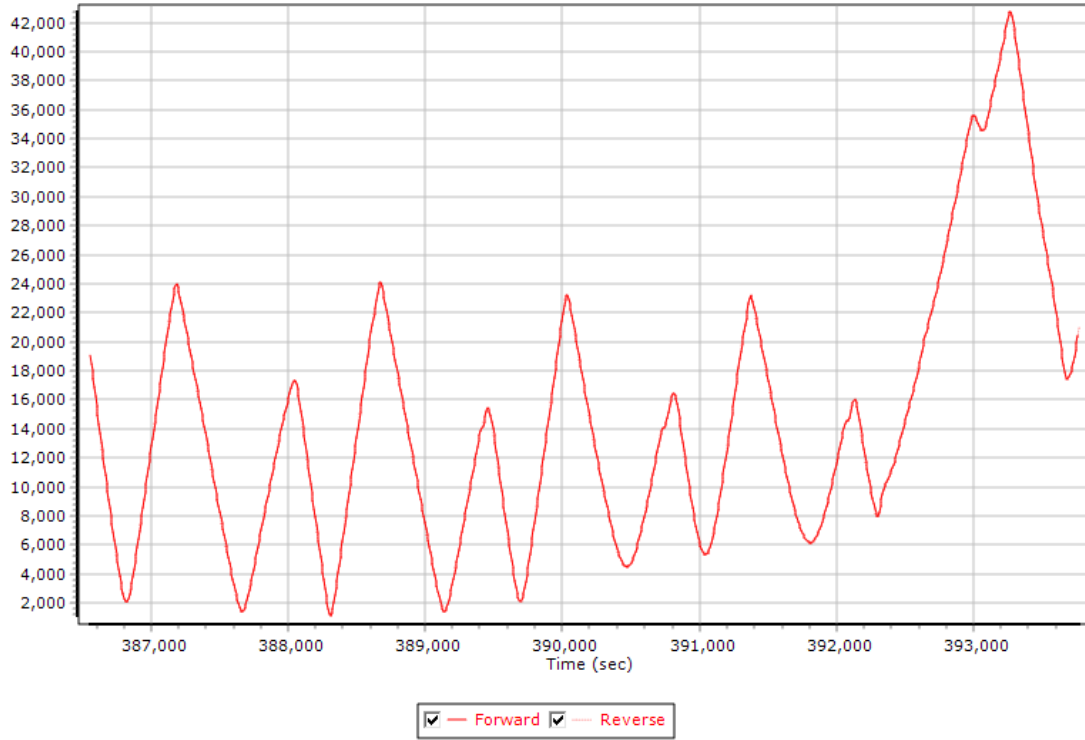


— North (m) — East (m) — Down (m) — DR mode

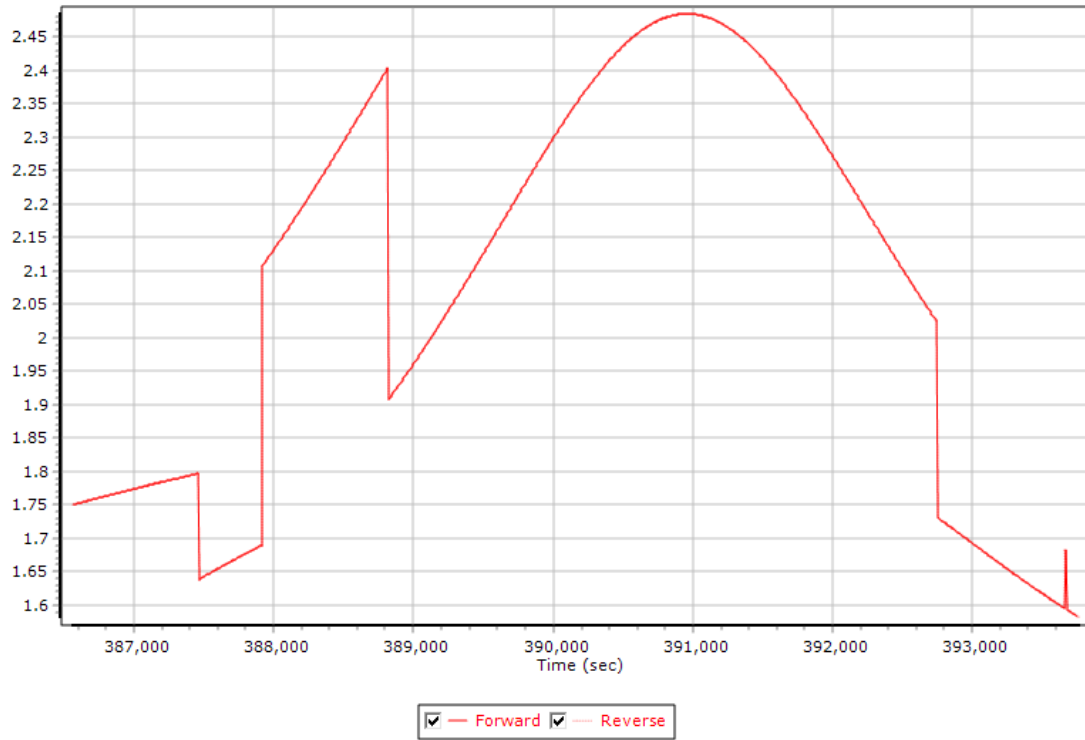


— Number of GPS Satellites — Number of GLONASS Satellites

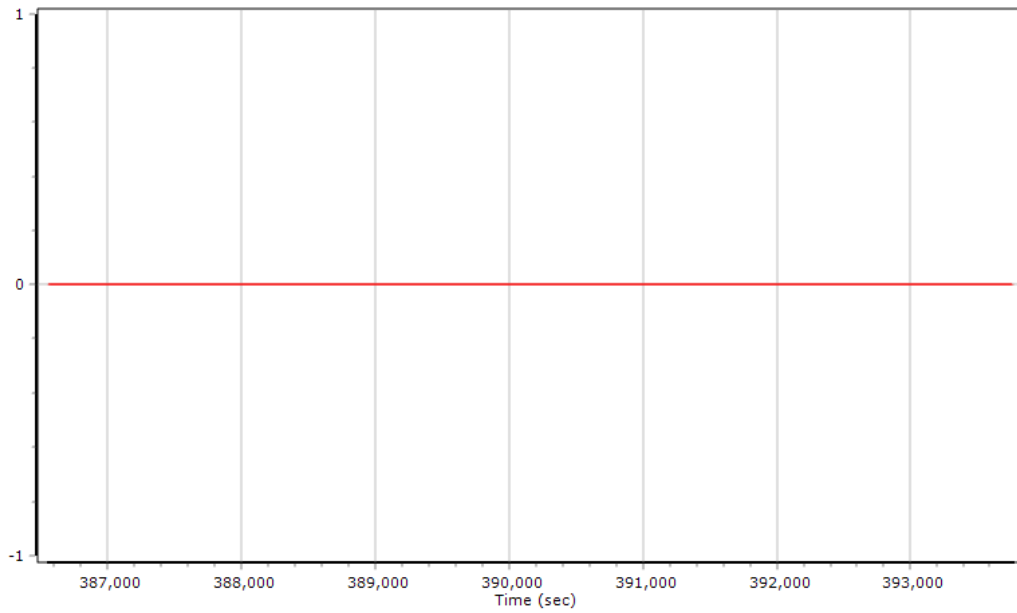
Baseline Length (m)



PDOP

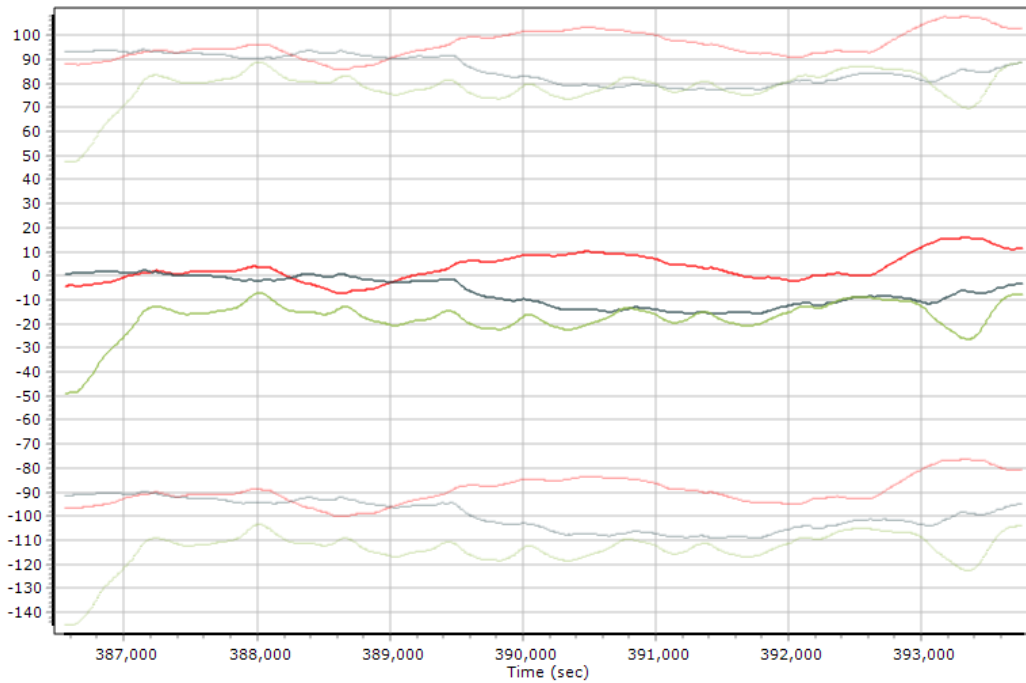


Processing mode

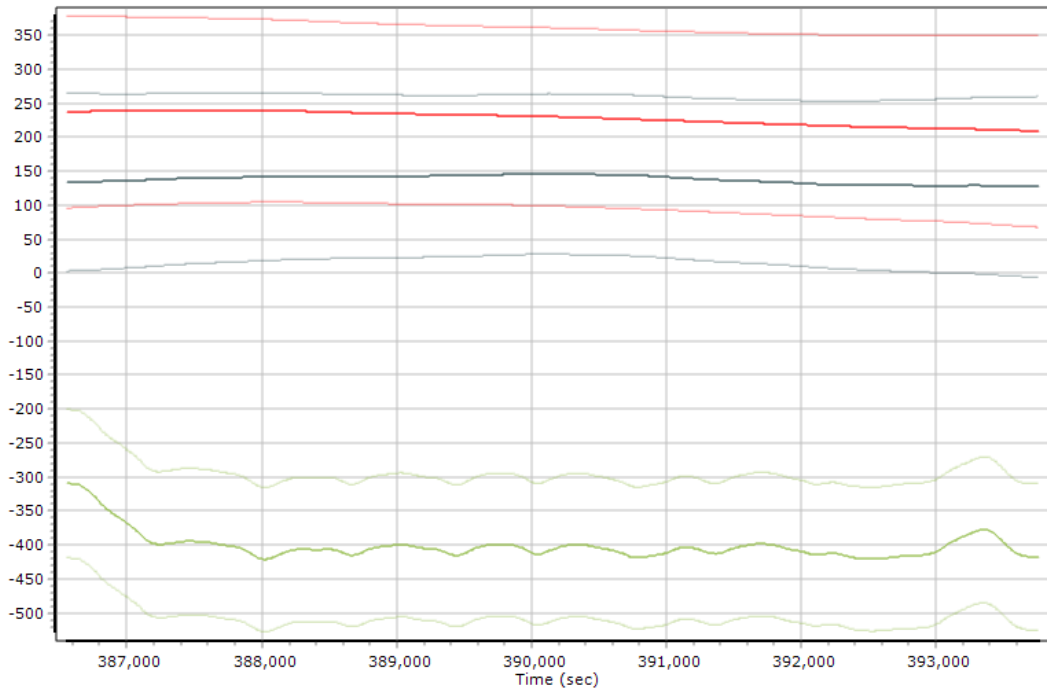


Forward Reverse

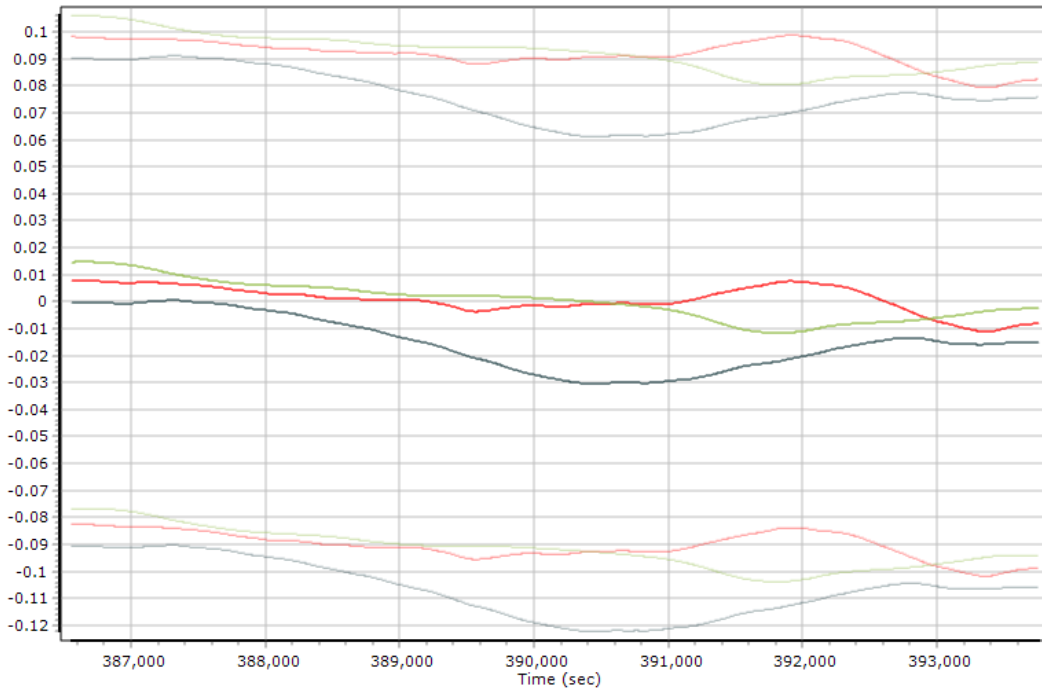
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



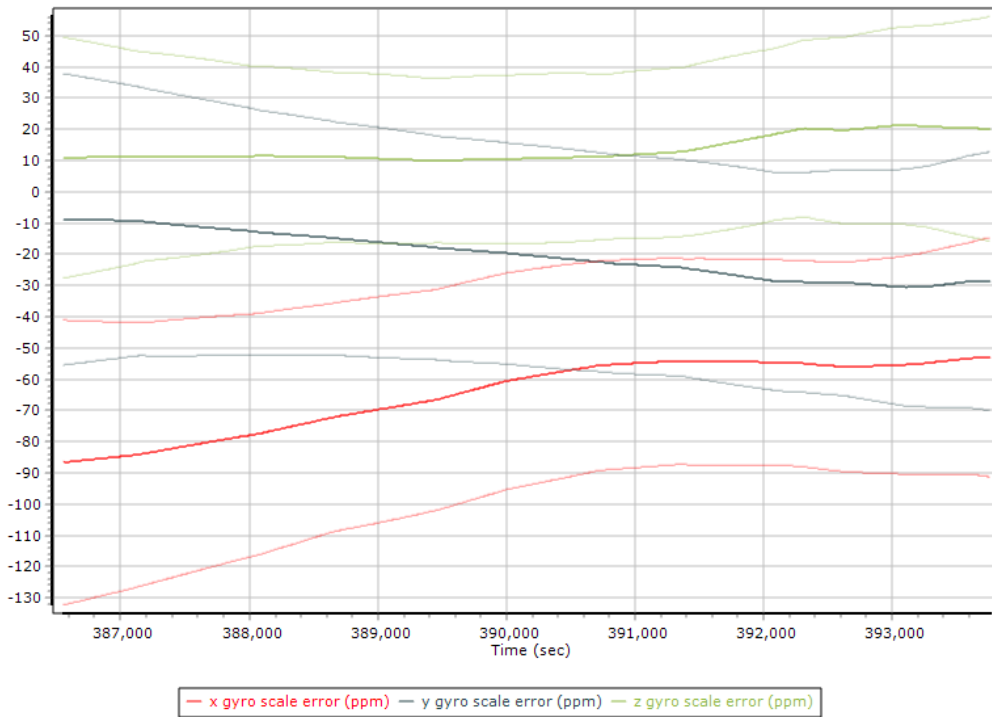
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



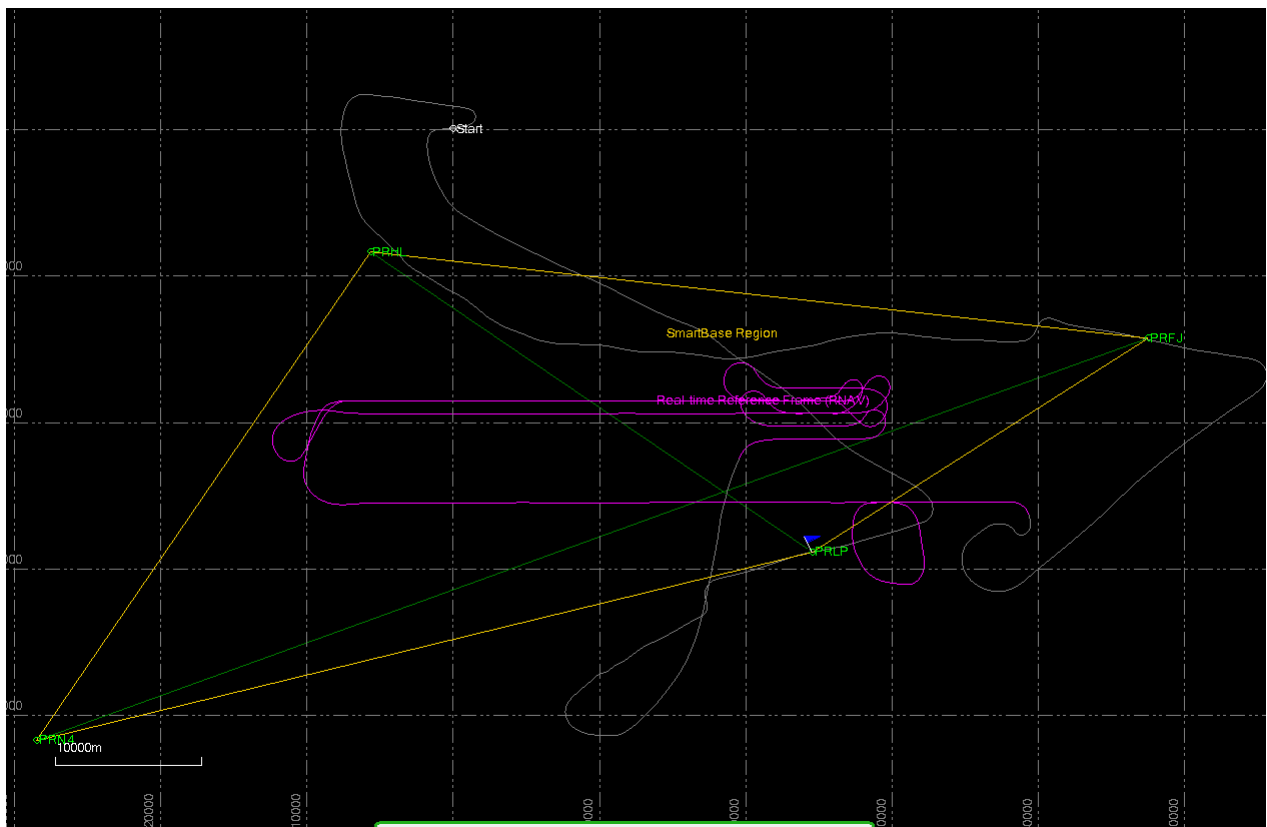
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

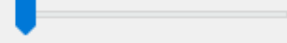


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

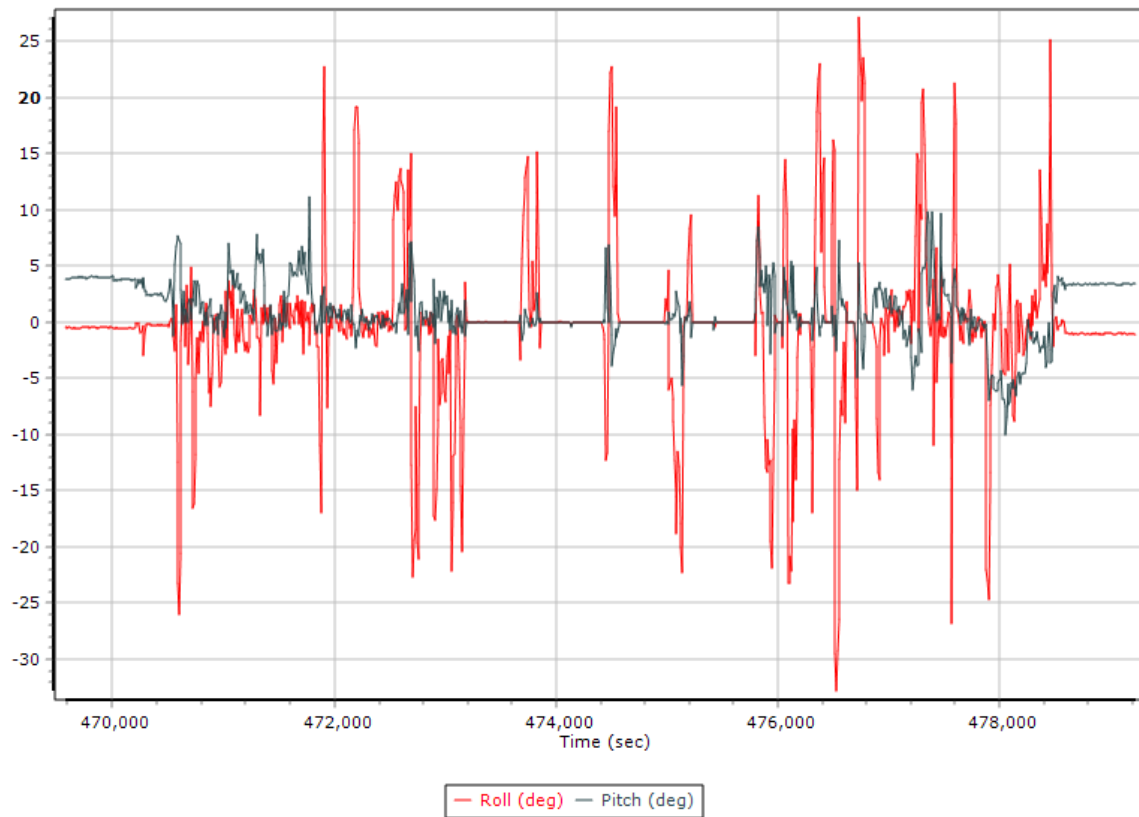
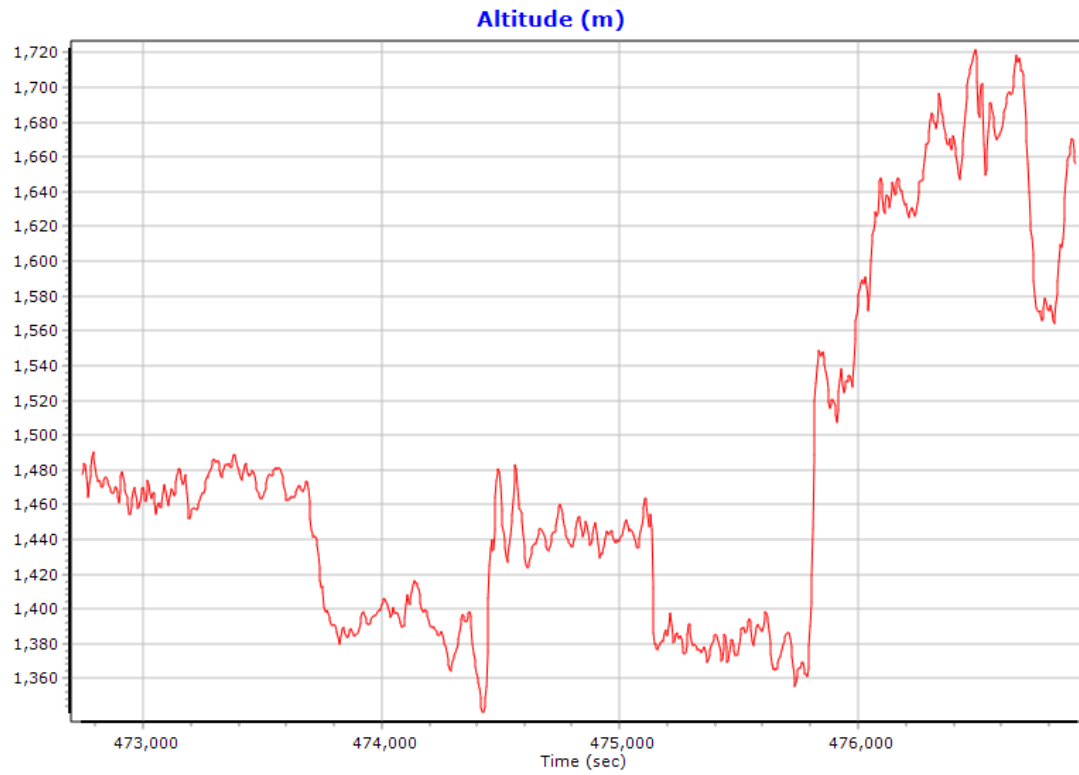


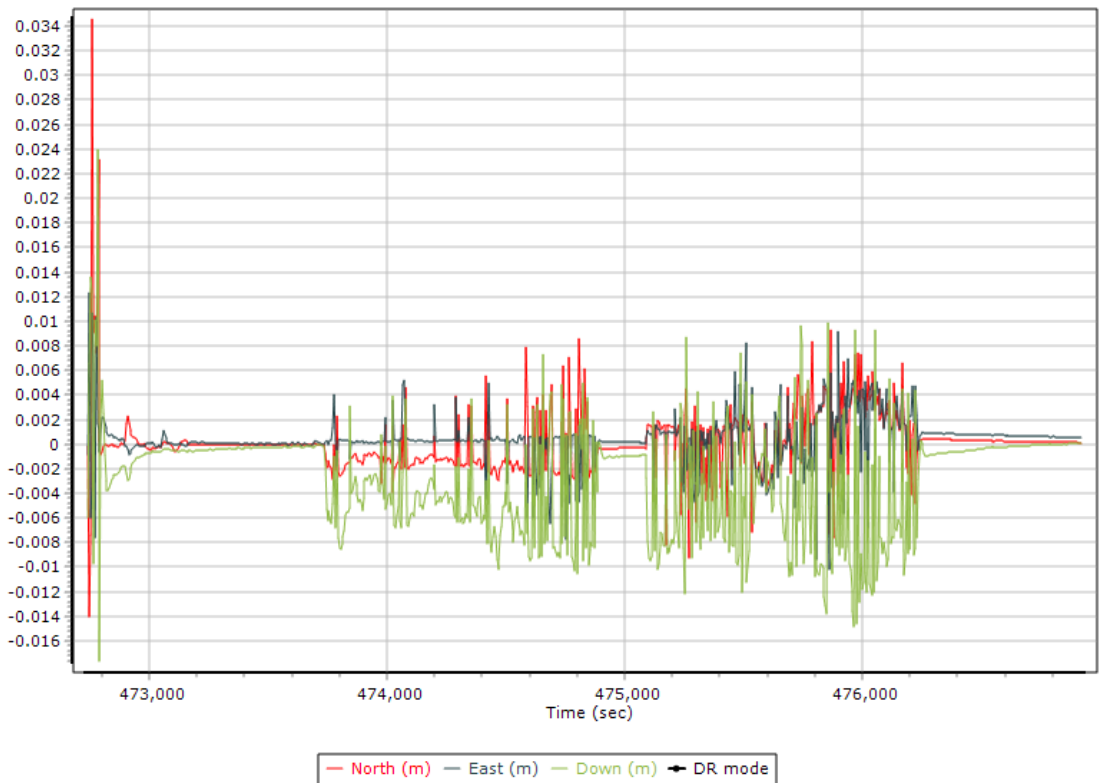
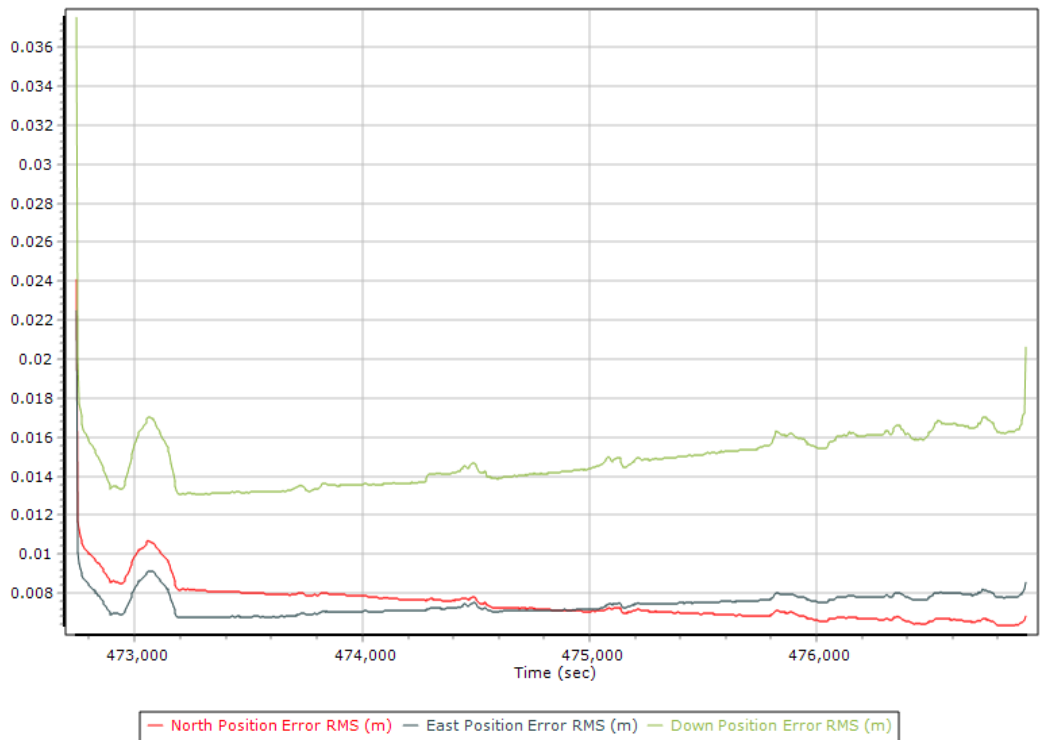
AZT18159A

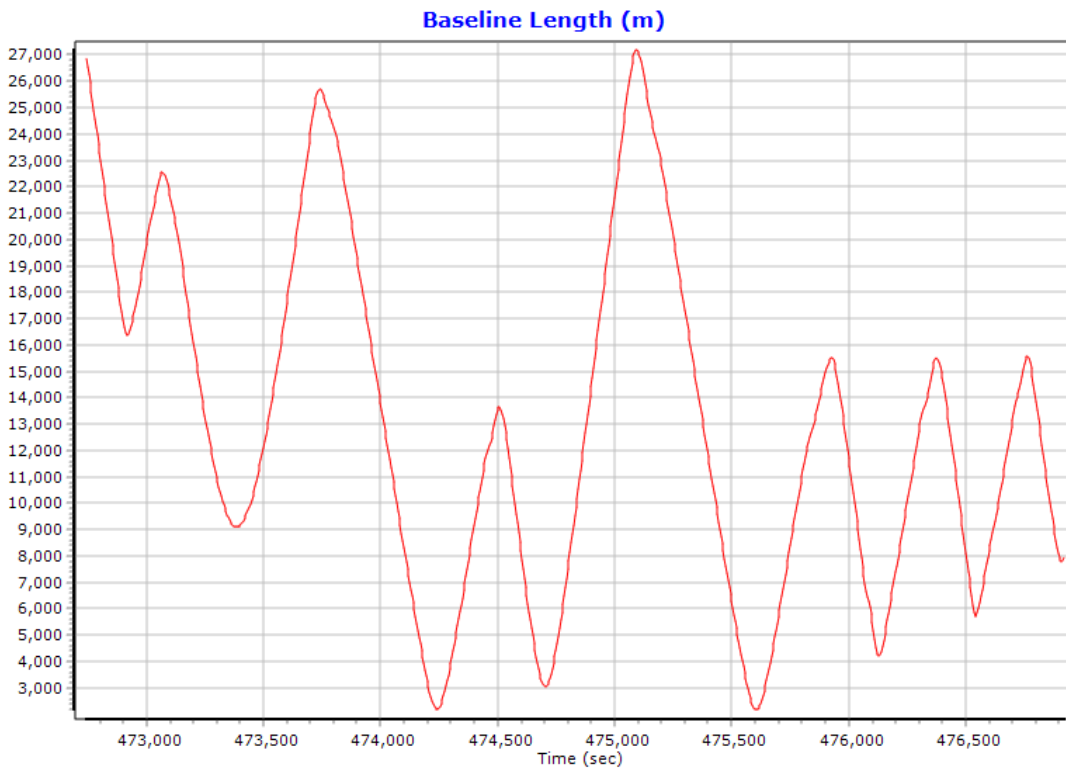
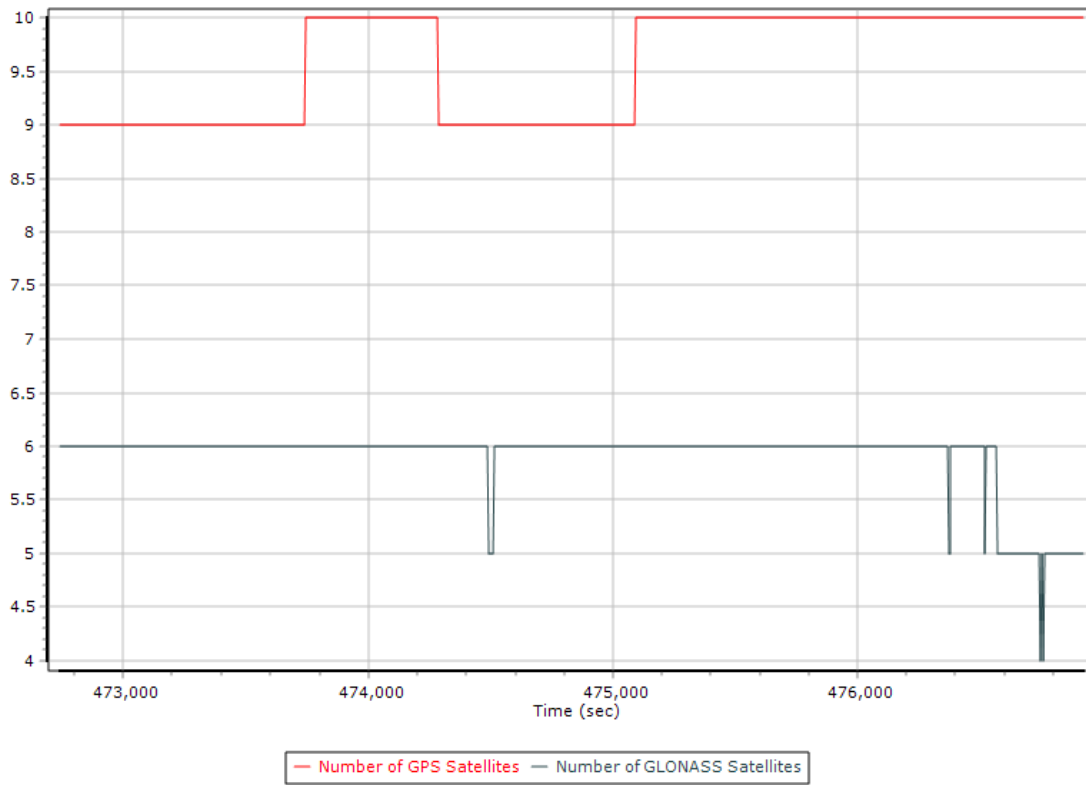


Stabilized Mount to IMU Lever Arm X <input type="text" value="-0.034 m"/> Y <input type="text" value="-0.010 m"/> Z <input type="text" value="-0.352 m"/>		Stabilized Mount to IMU Mounting Angles X <input type="text" value="0.000 deg"/> Y <input type="text" value="0.000 deg"/> Z <input type="text" value="0.000 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="-0.738 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  <input type="radio"/> <3cm <input type="radio"/> 10cm <input type="radio"/> 50cm <input type="radio"/> 1m <input type="radio"/> 10m			
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.			

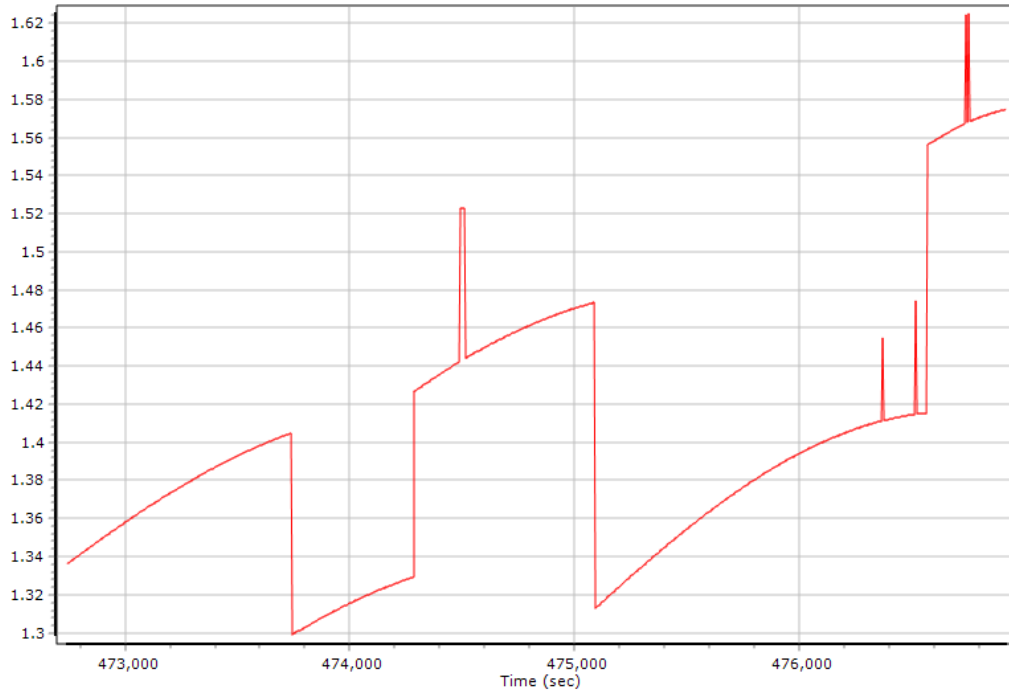
Timing										
Start	<input type="text" value="6/8/2018 11:19:01 AM"/>									
End	<input type="text" value="6/8/2018 12:28:43 PM"/>									
<input type="checkbox"/>	Entire time interval									
<input type="checkbox"/>	Seconds of start week									
UTC Offset	<input type="text" value="18.000"/>									
	<table border="1"> <thead> <tr> <th>Data</th> <th>Incr. (sec)</th> </tr> </thead> <tbody> <tr> <td>Output Record</td> <td>0.005000</td> </tr> <tr> <td>IMU</td> <td>0.005000</td> </tr> <tr> <td>Primary GNSS</td> <td>1.000000</td> </tr> </tbody> </table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000	
Data	Incr. (sec)									
Output Record	0.005000									
IMU	0.005000									
Primary GNSS	1.000000									



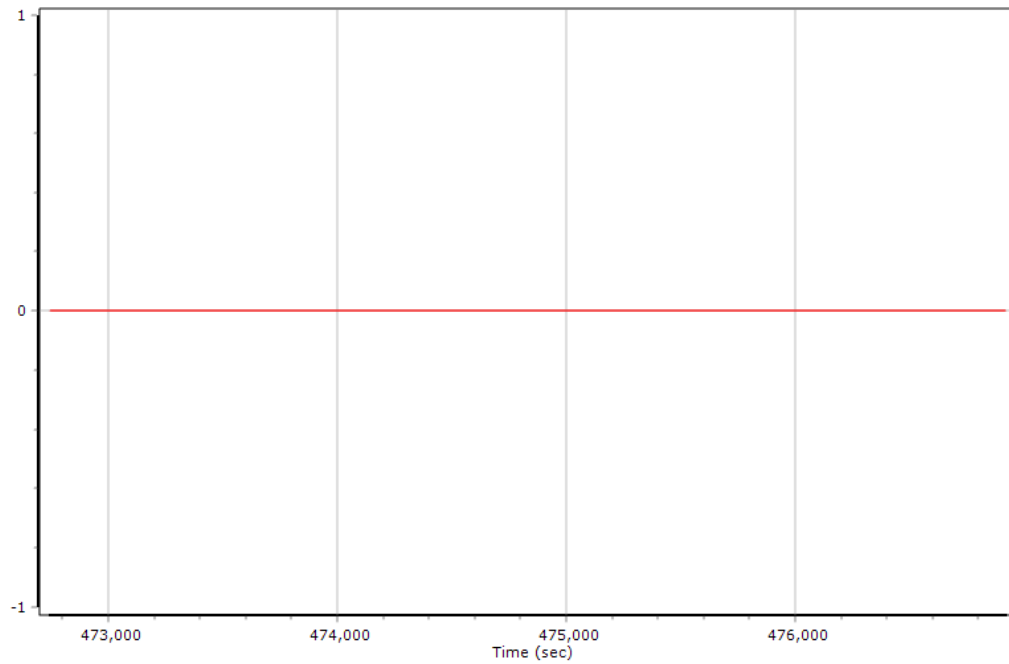




PDOP

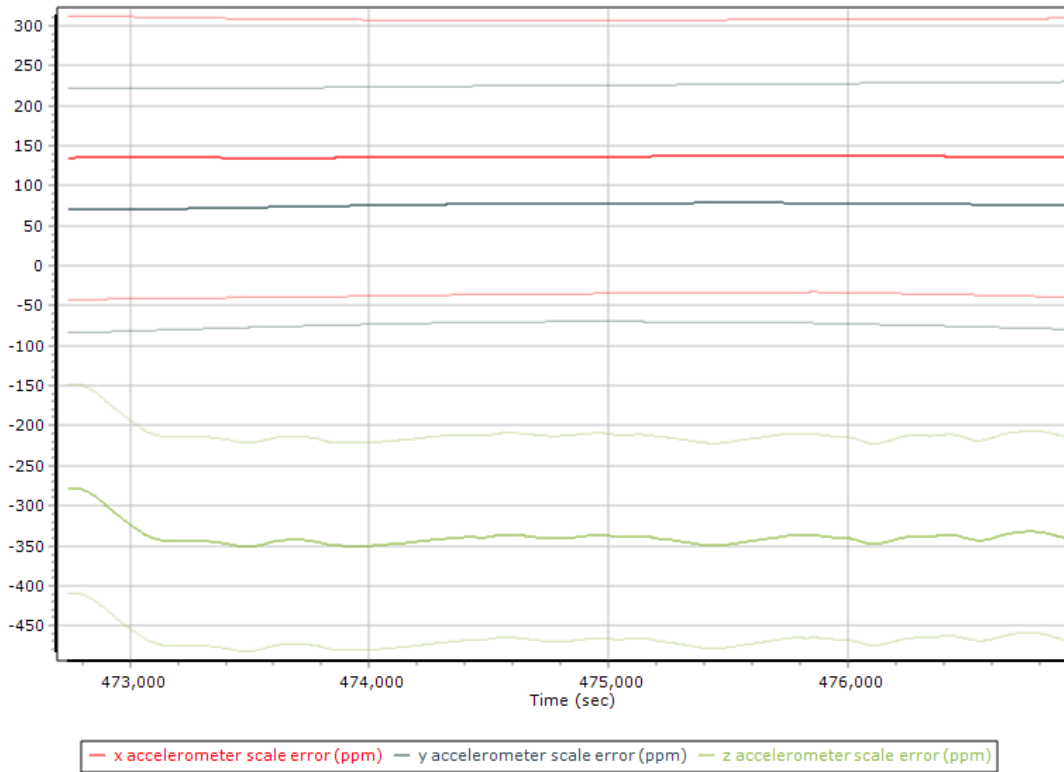
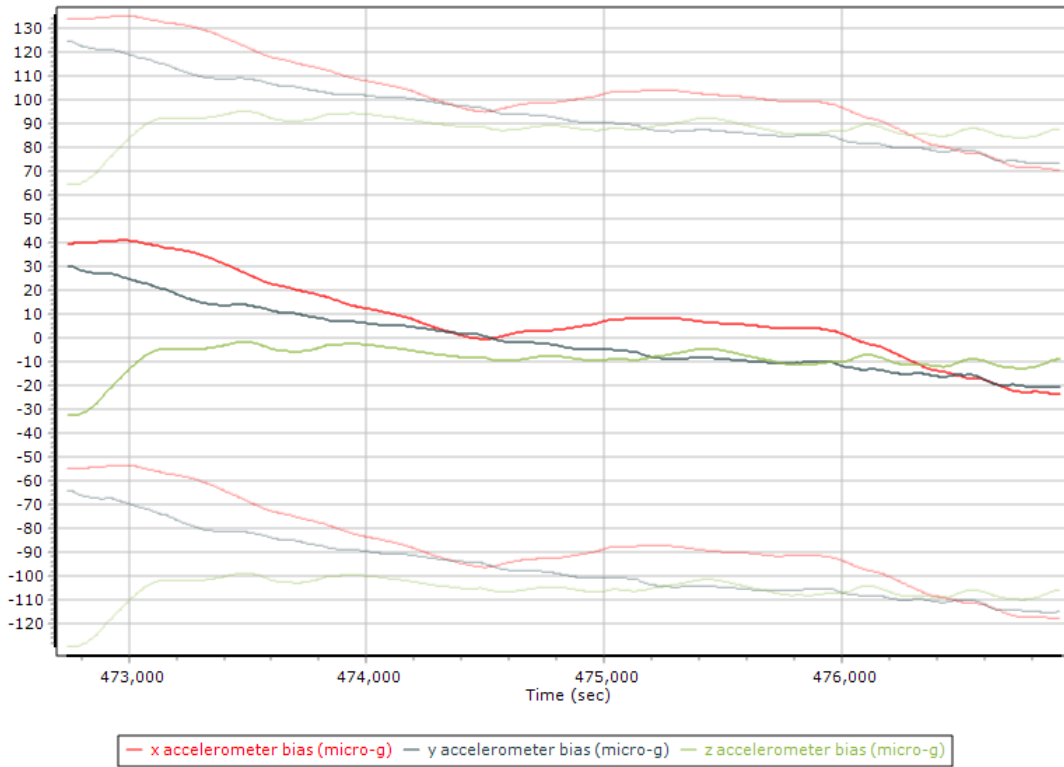


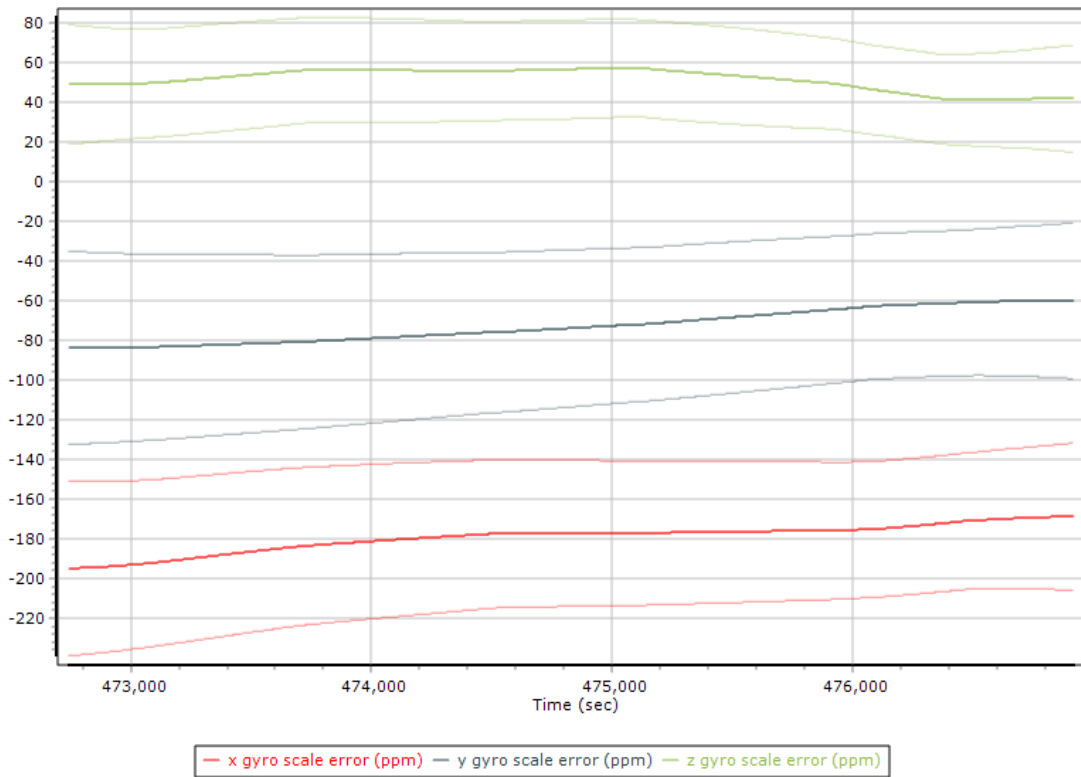
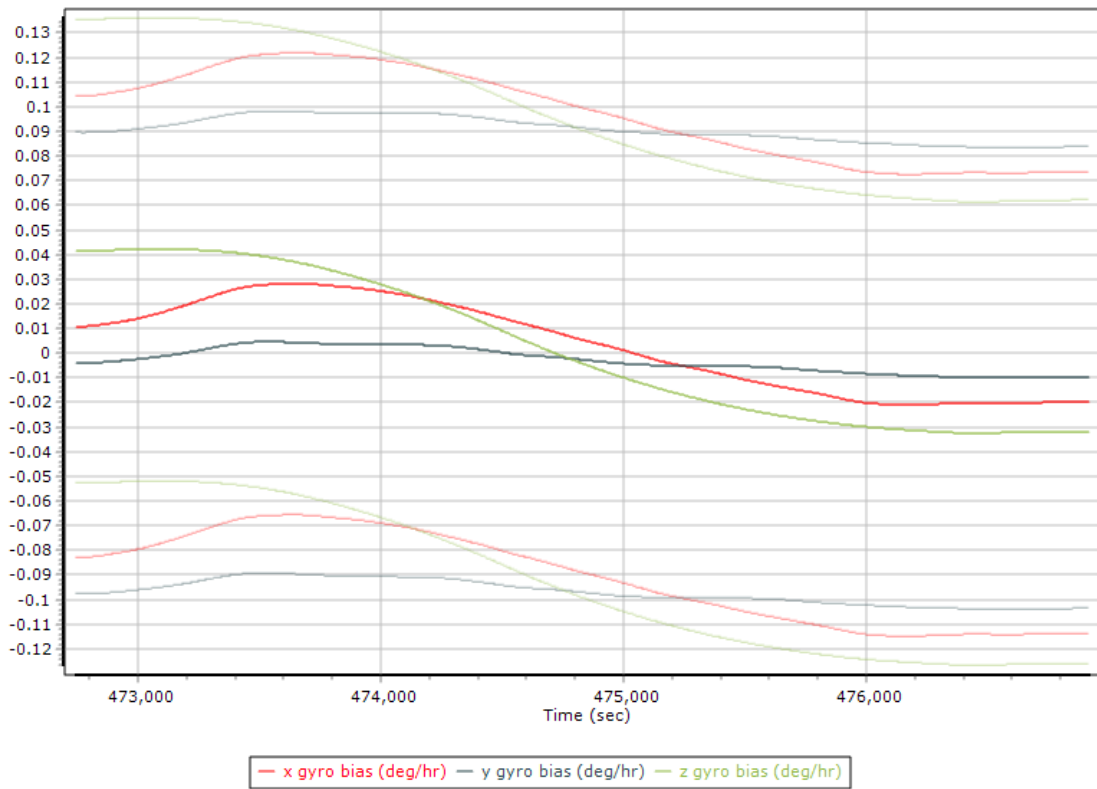
Processing mode



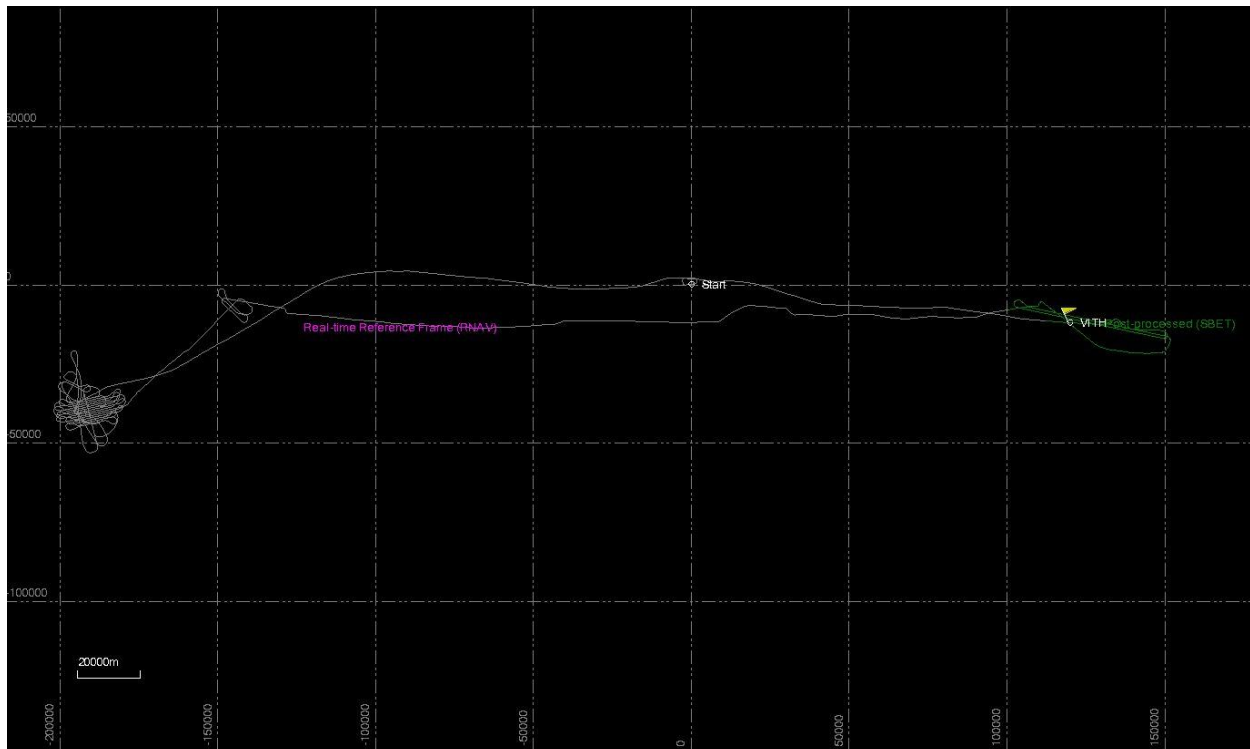
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

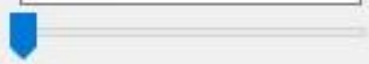
Sensor Errors





AZT18159B1



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="checkbox"/> <3cm <input type="checkbox"/> 10cm <input type="checkbox"/> 50cm <input type="checkbox"/> 1m <input type="checkbox"/> 10m			

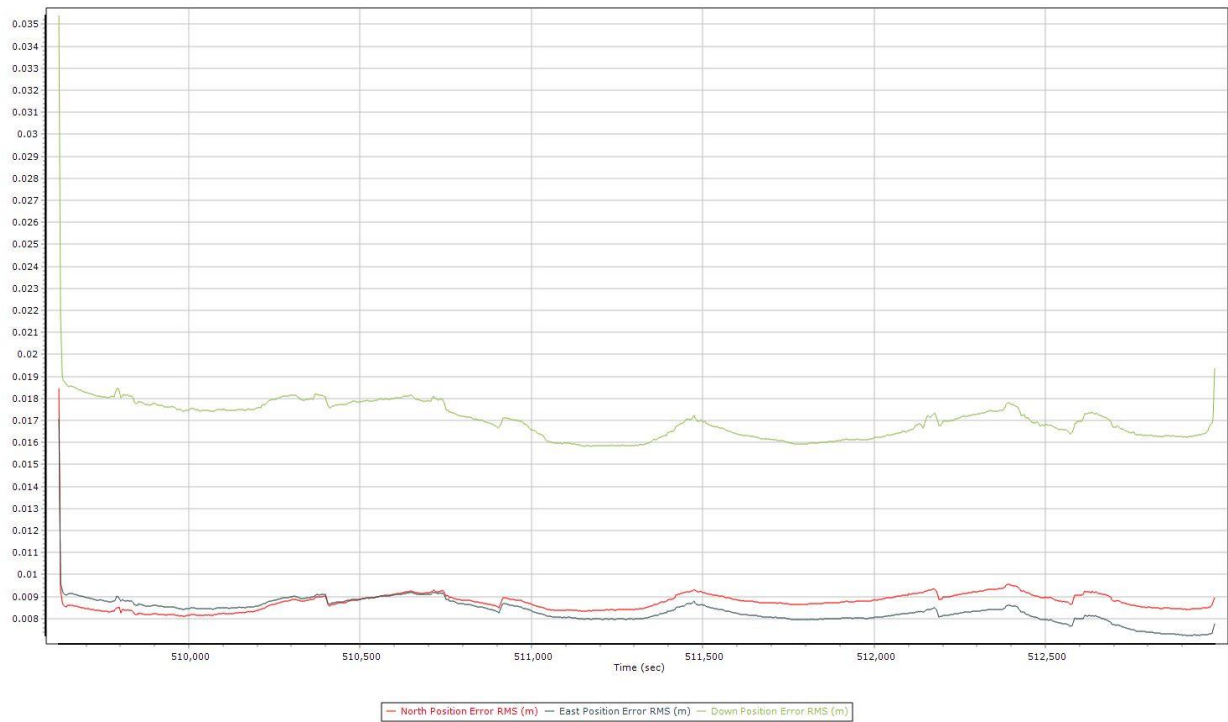
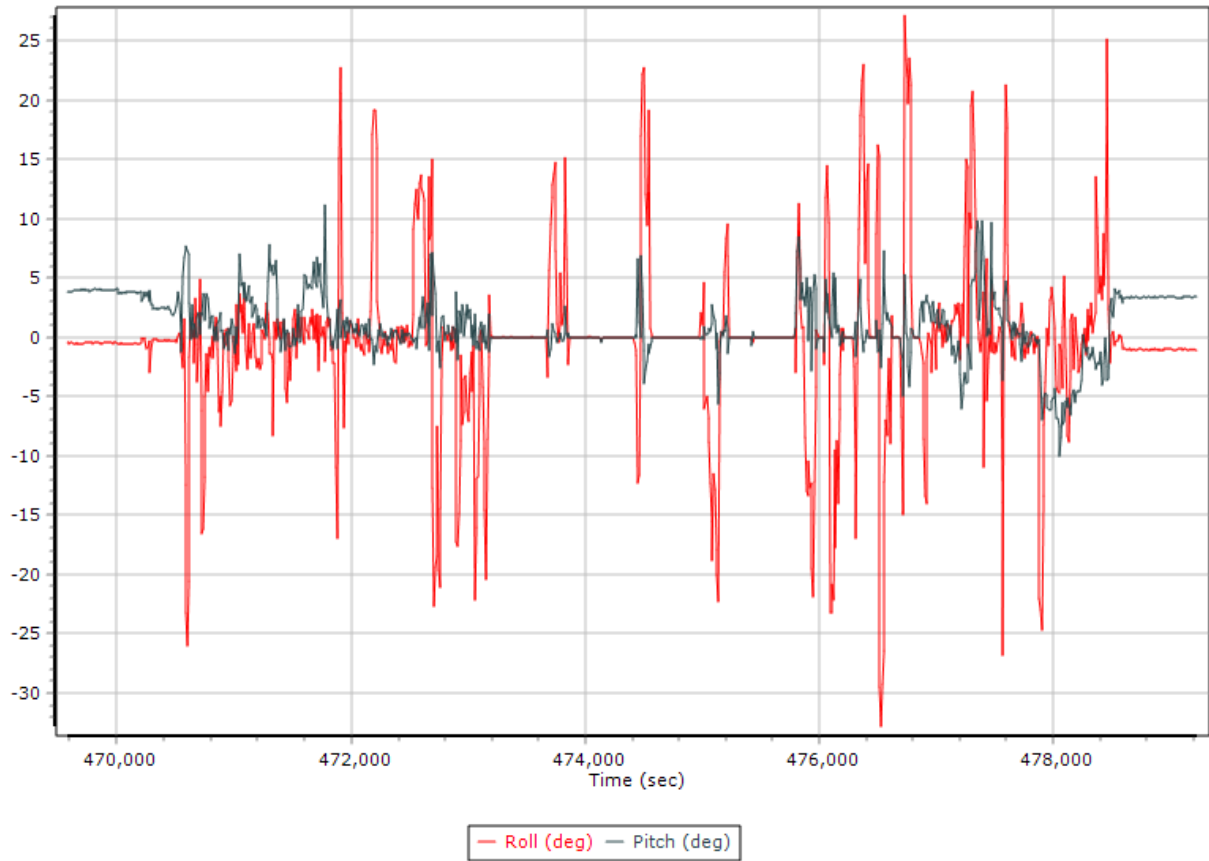
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

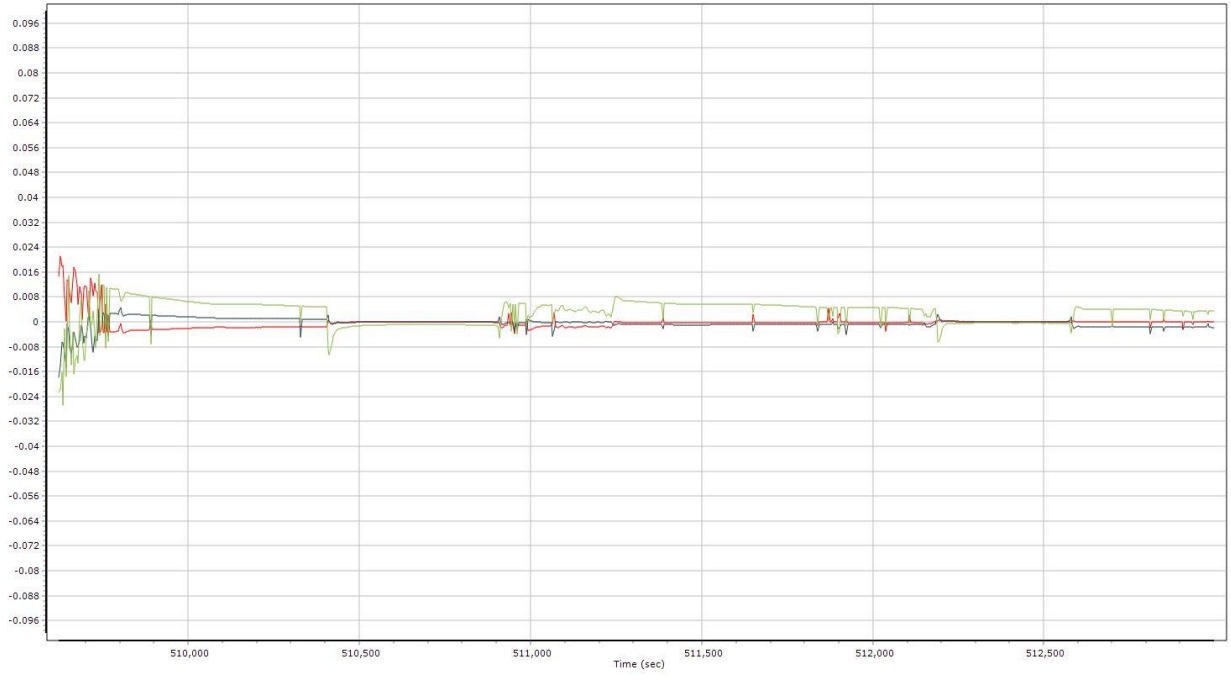
Timing

Start	509618.955	Data	Incr. (sec)
End	512999.747	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

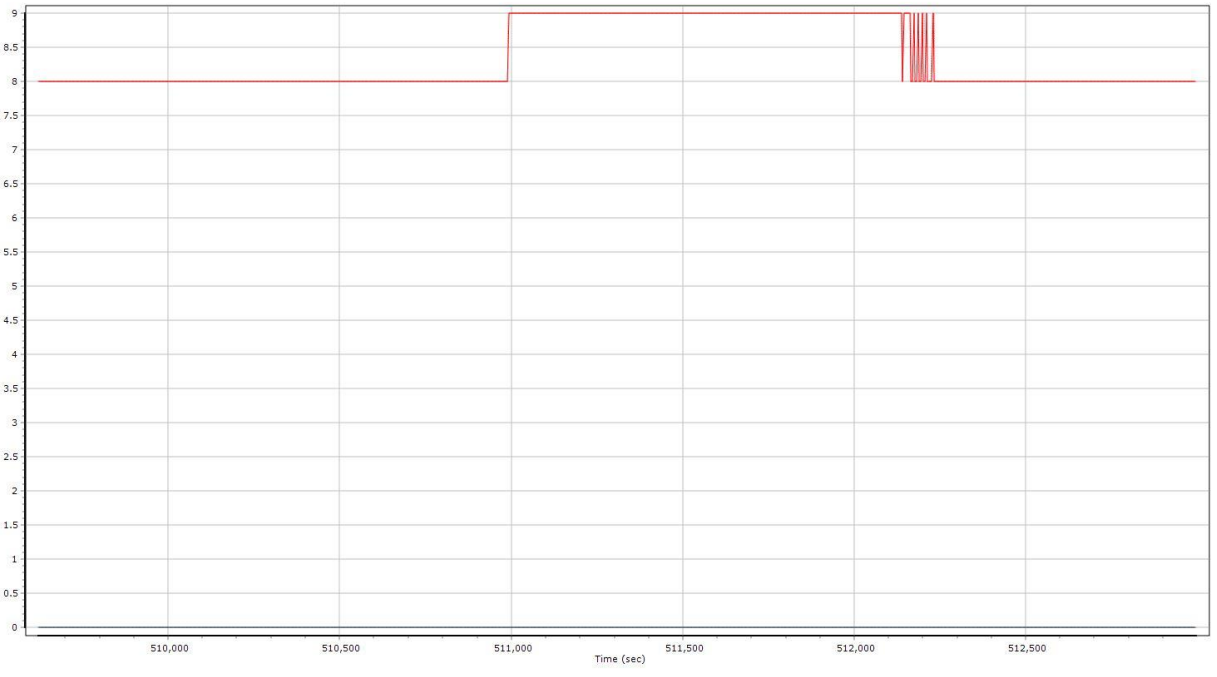
UTC Offset 18.000



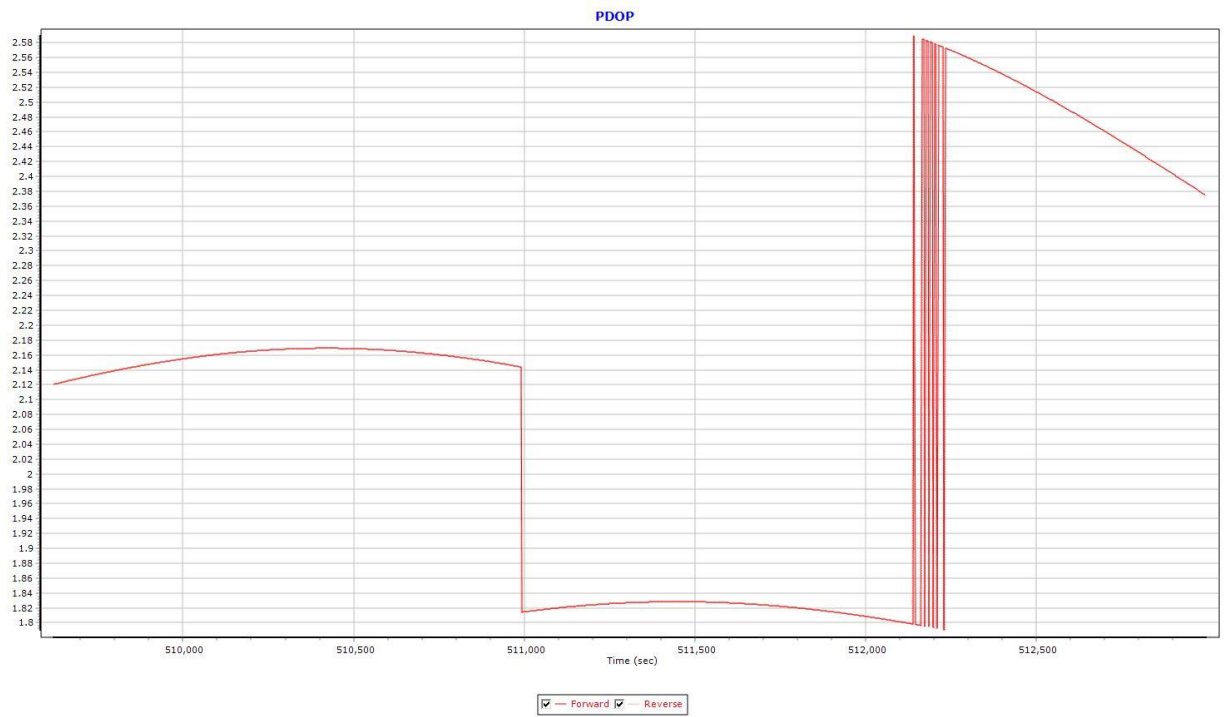
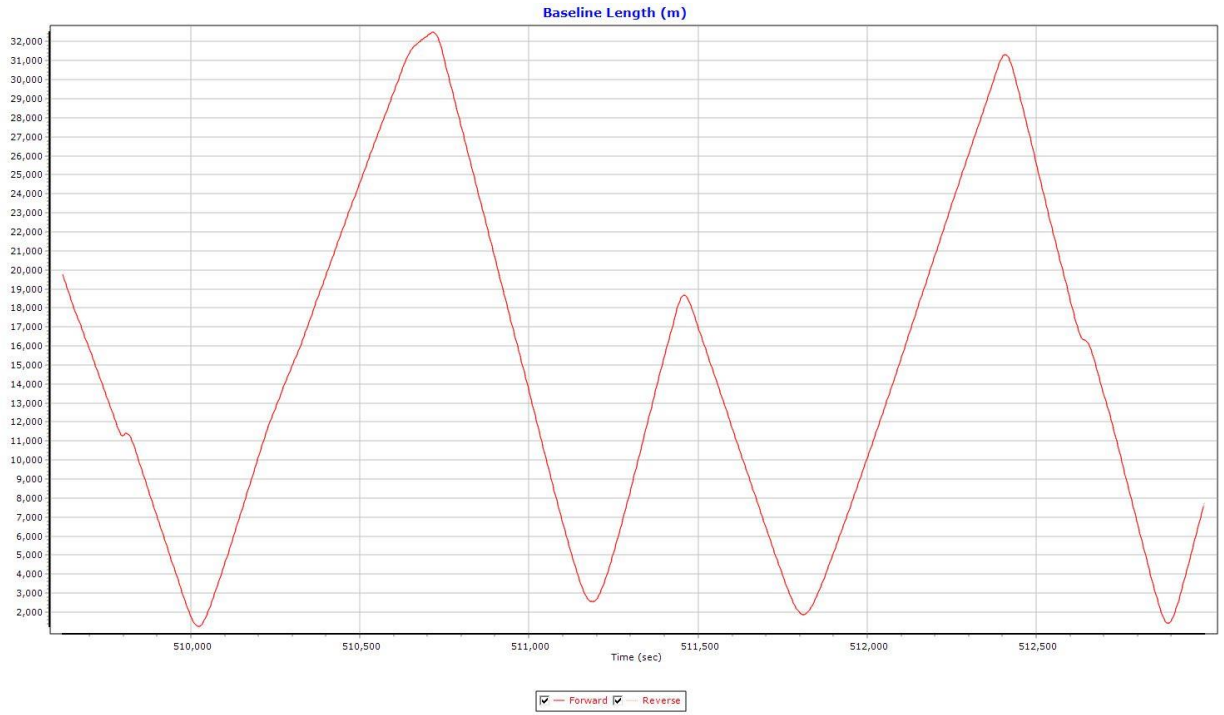


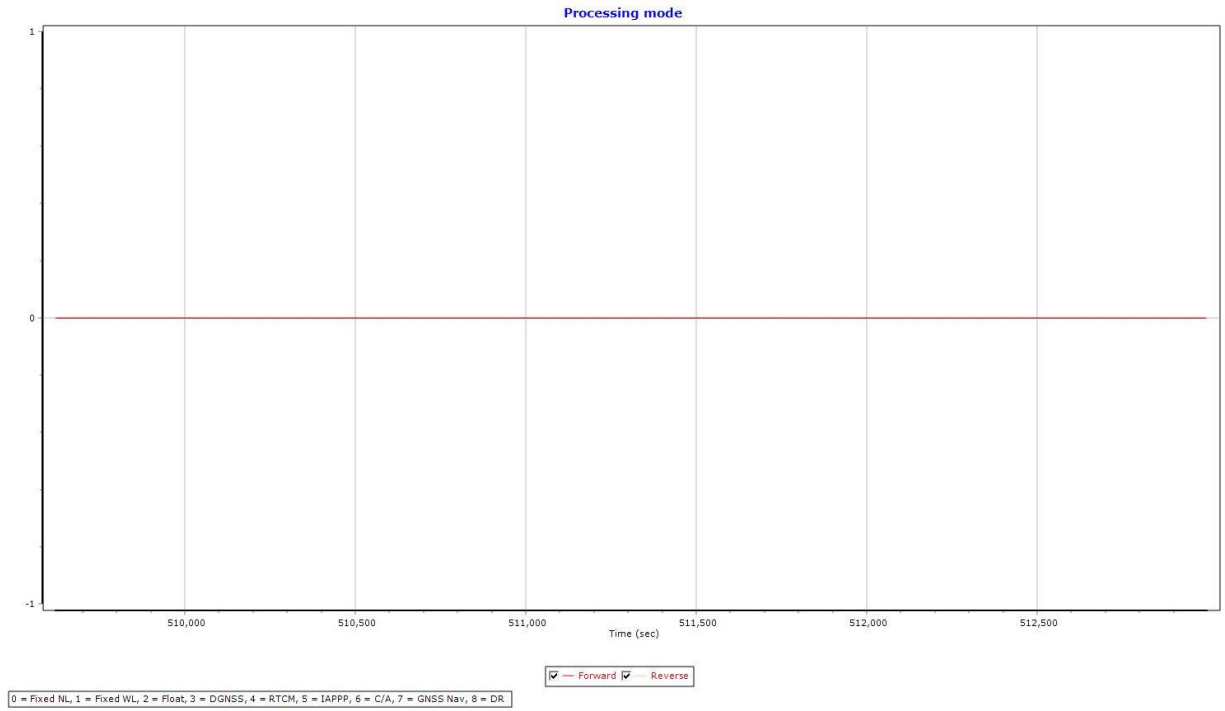


— North (m) — East (m) — Down (m) — DR mode

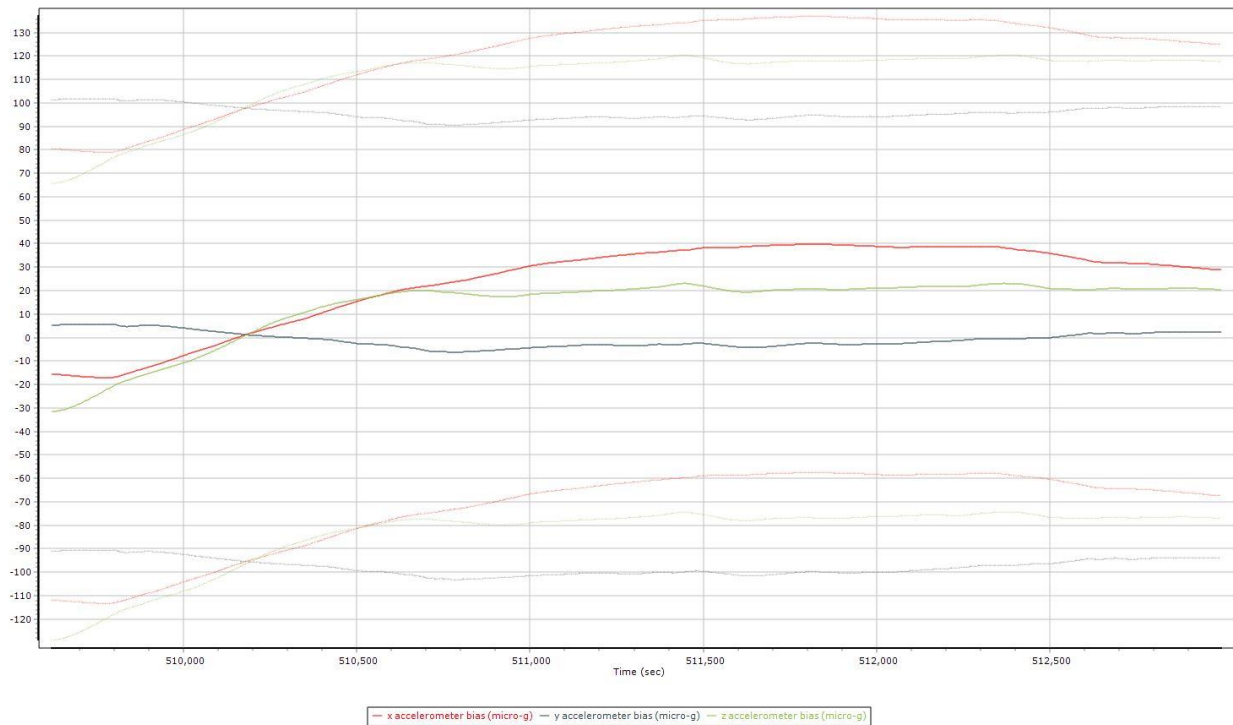


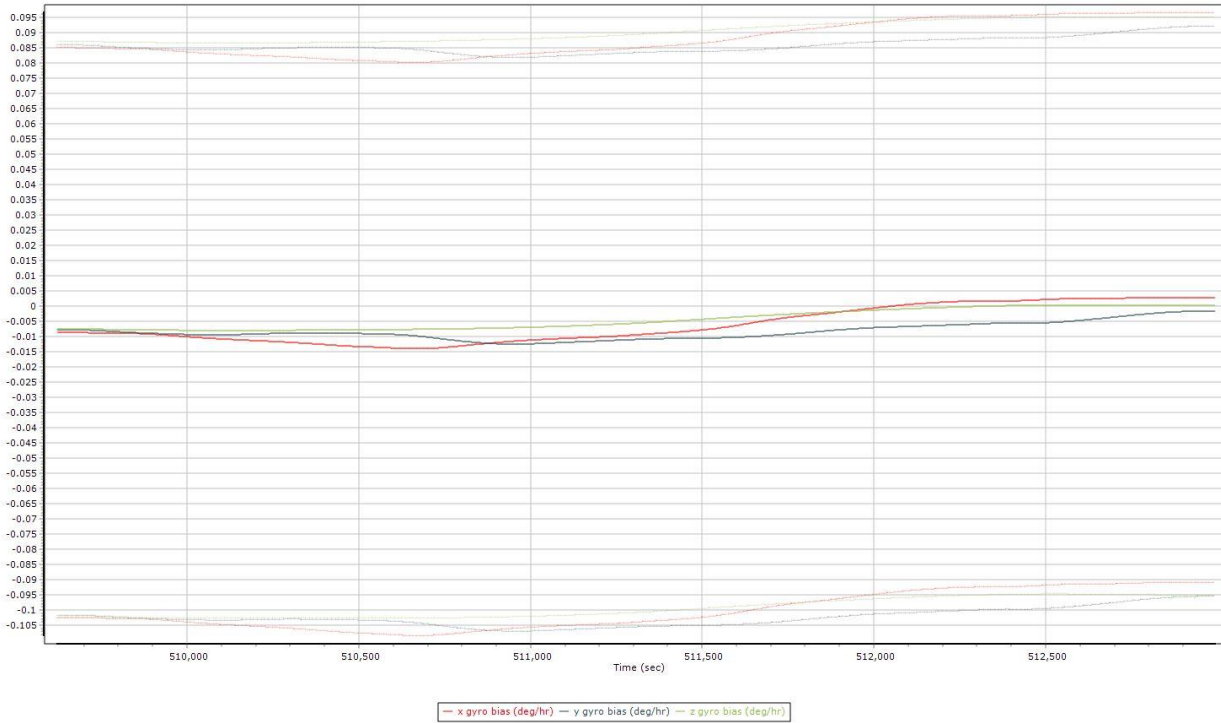
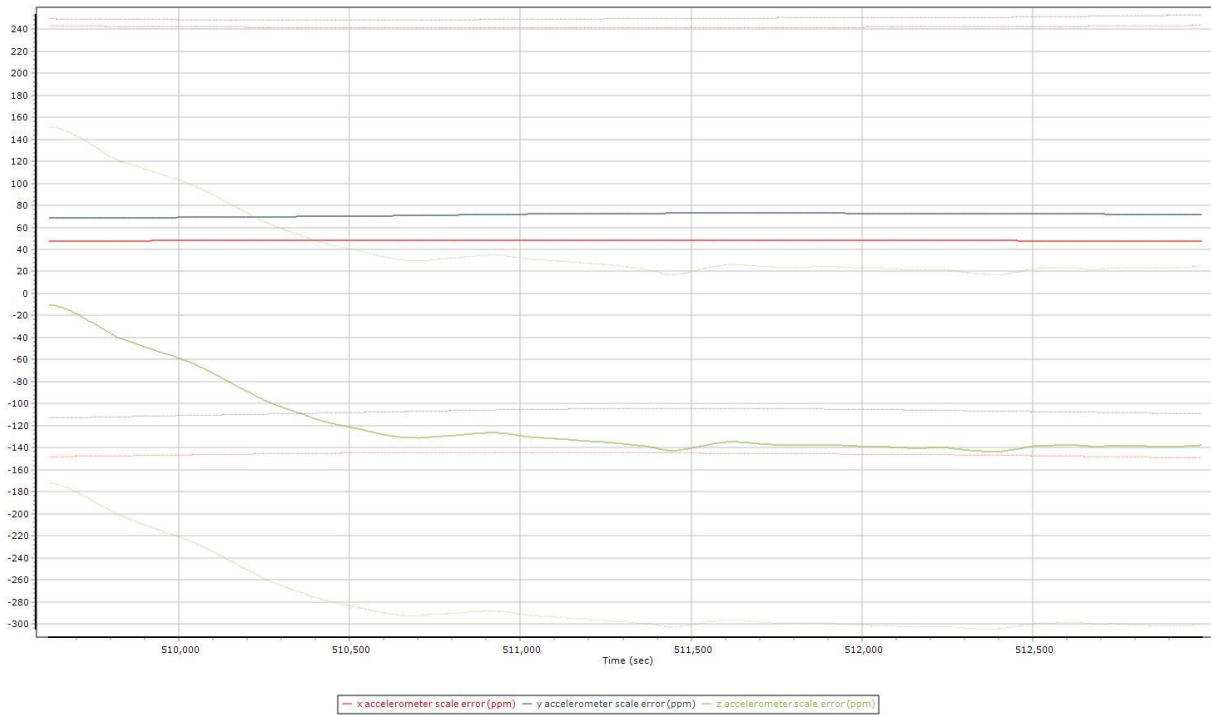
— Number of GPS Satellites — Number of GLONASS Satellites

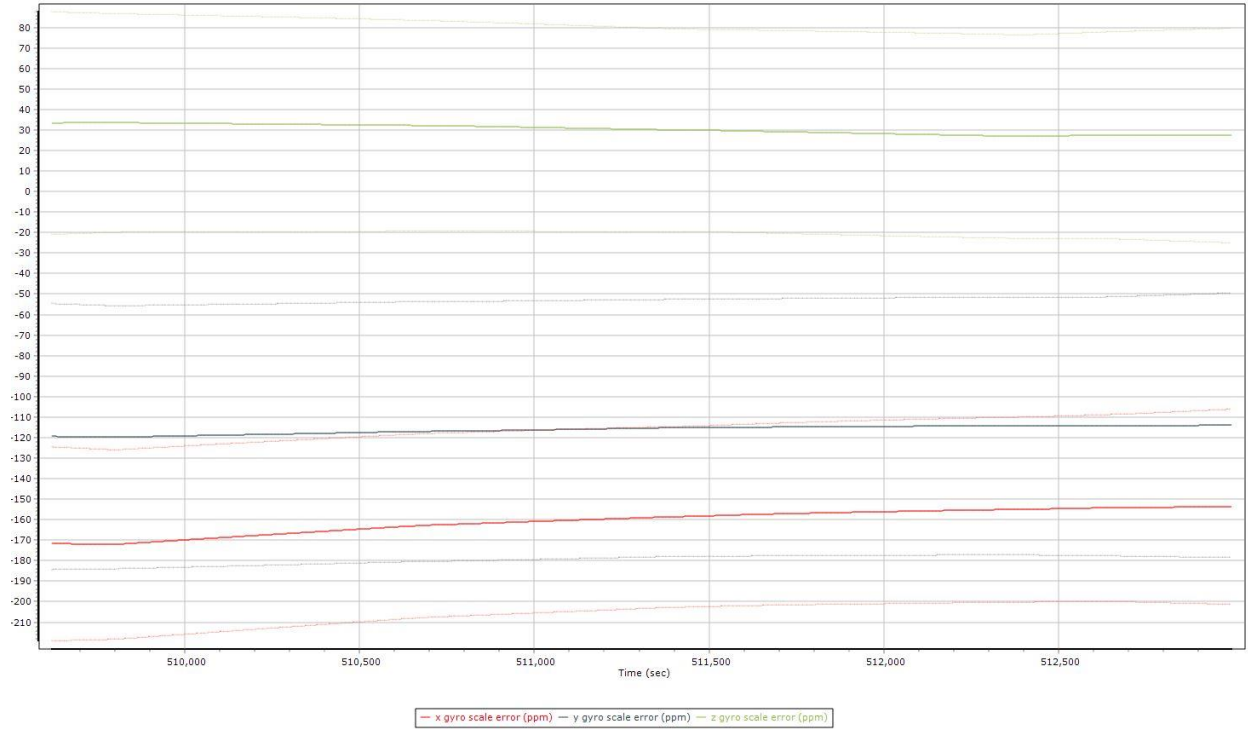




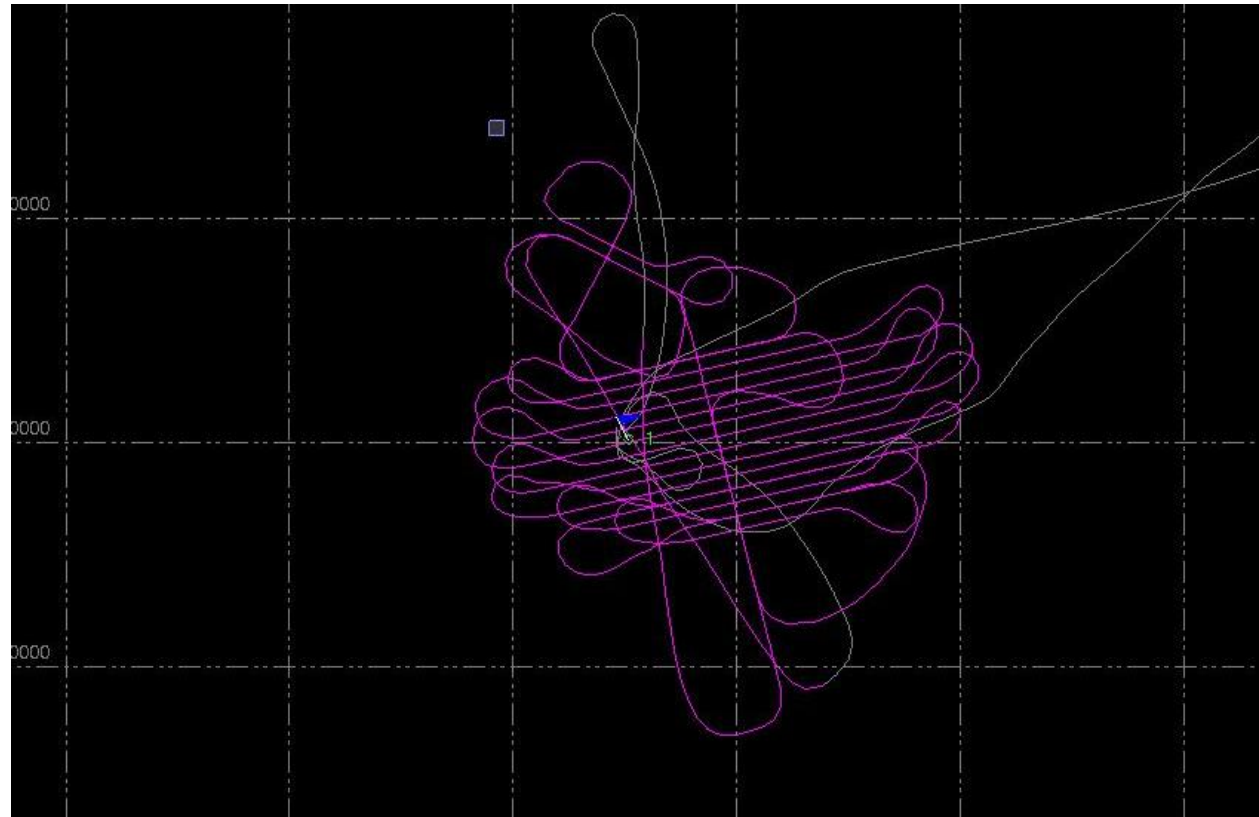
Sensor Errors

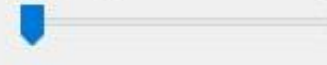




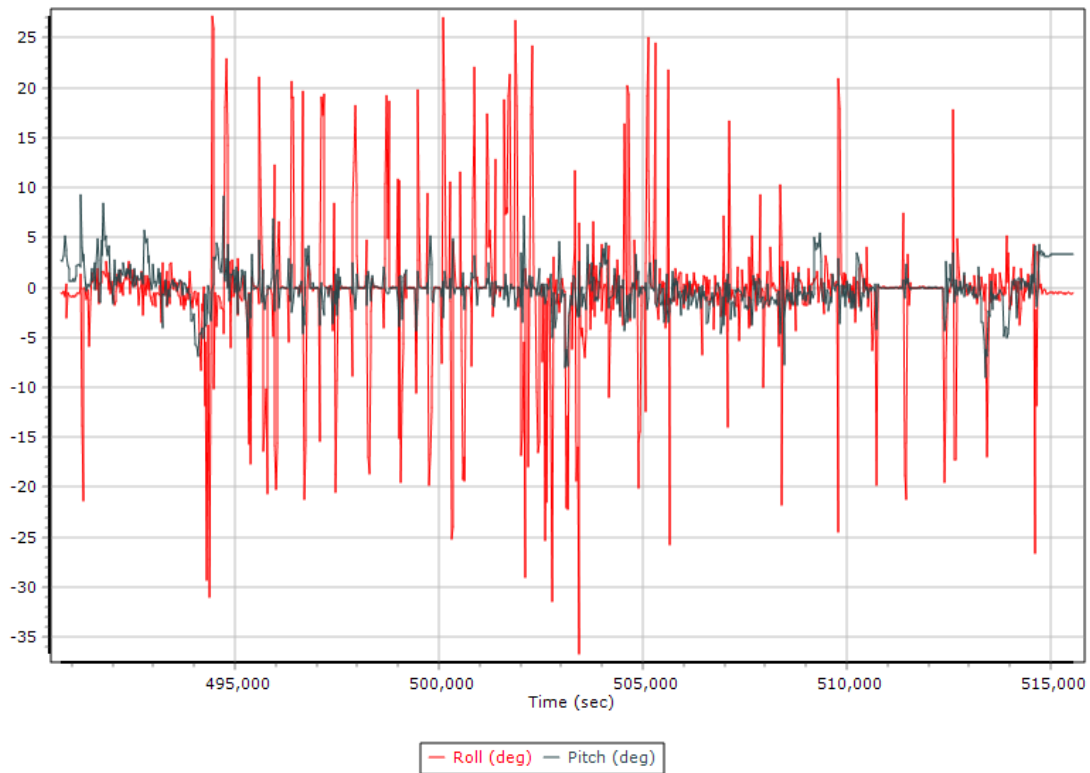
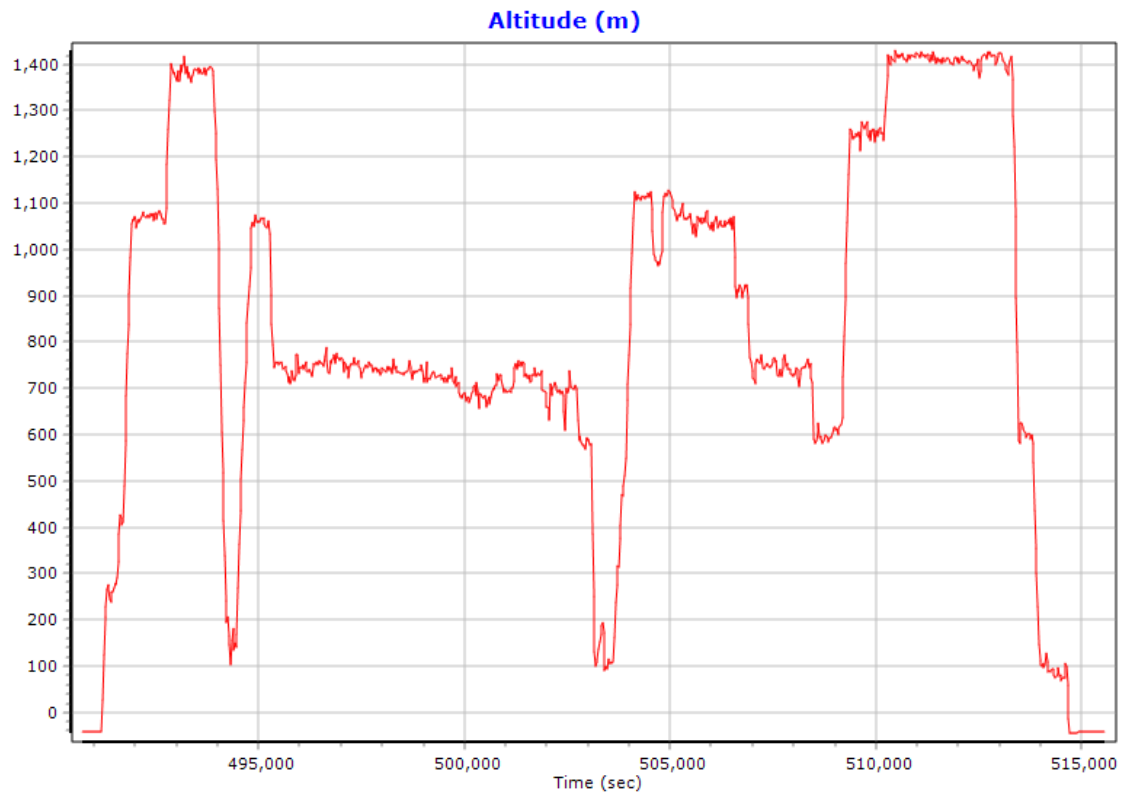


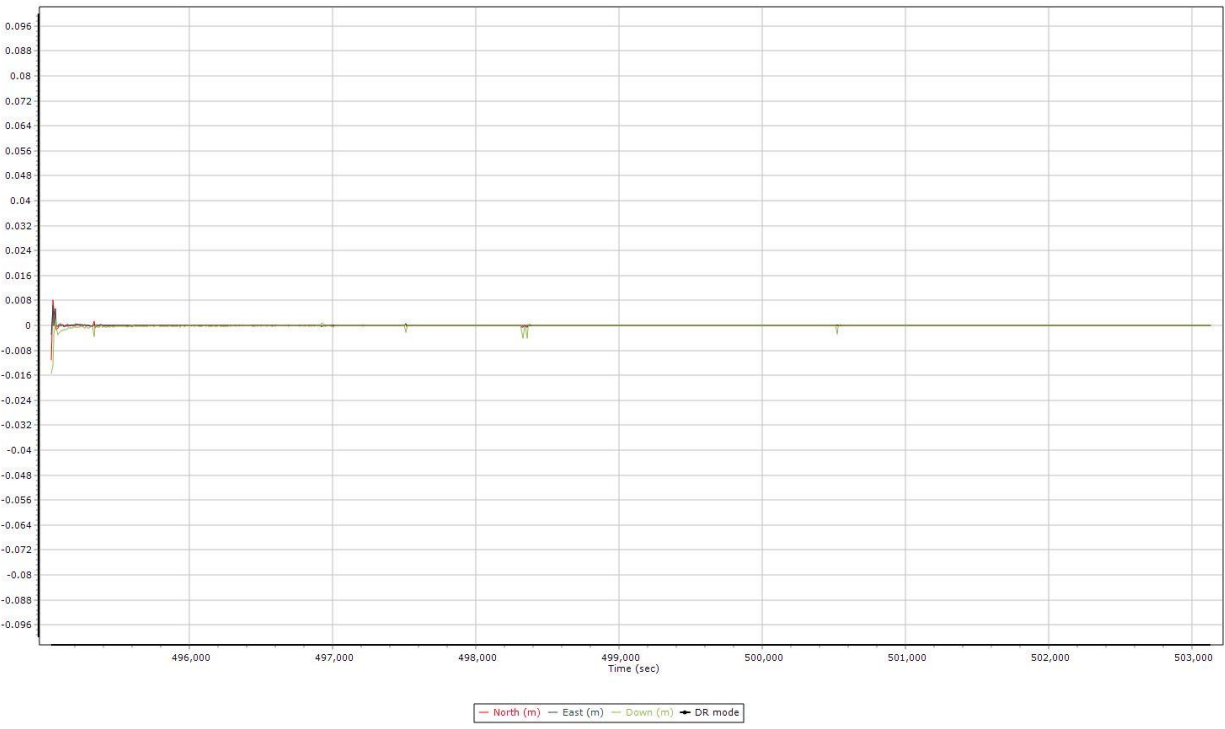
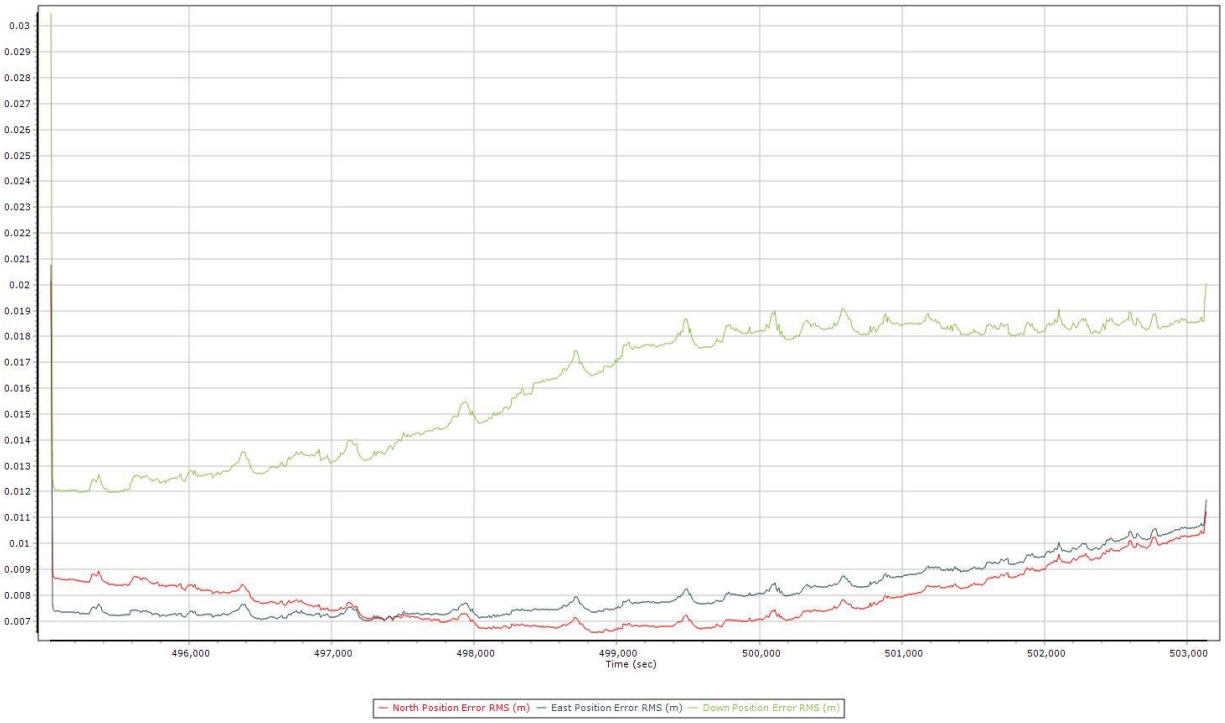
AZT18159B2



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"/> Standard Deviation 		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"/>	
<3cm 10cm 50cm 1m 10m			
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.			

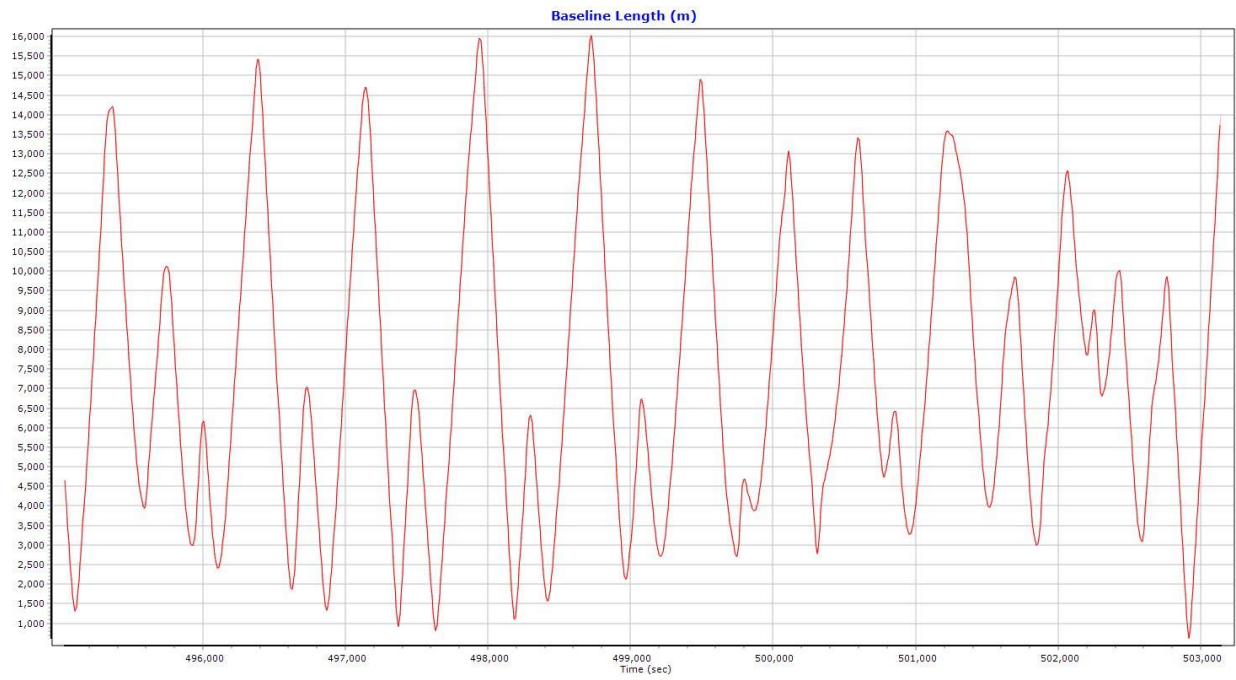
Timing Start <input type="text" value="495031.827"/> End <input type="text" value="503143.734"/> <input type="checkbox"/> Entire time interval <input checked="" type="checkbox"/> Seconds of start week UTC Offset <input type="text" value="18.000"/>		<table border="1"> <thead> <tr> <th>Data</th> <th>Incr. (sec)</th> </tr> </thead> <tbody> <tr> <td>Output Record</td> <td>0.005000</td> </tr> <tr> <td>IMU</td> <td>0.005000</td> </tr> <tr> <td>Primary GNSS</td> <td>1.000000</td> </tr> </tbody> </table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000
Data	Incr. (sec)									
Output Record	0.005000									
IMU	0.005000									
Primary GNSS	1.000000									



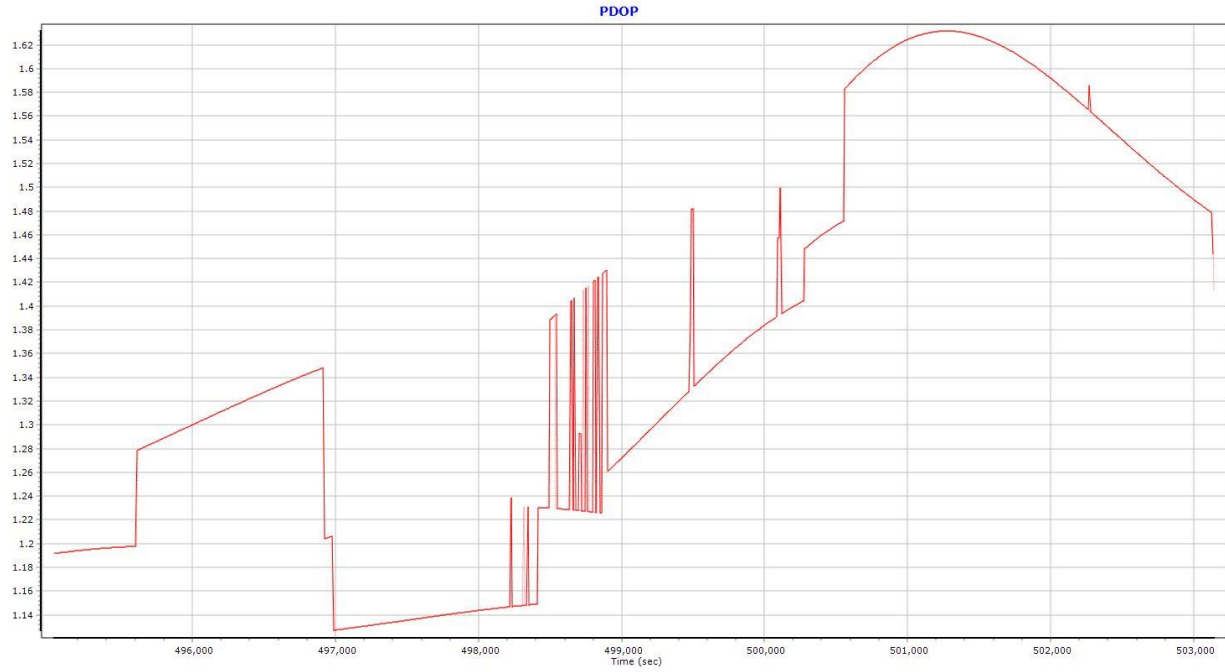




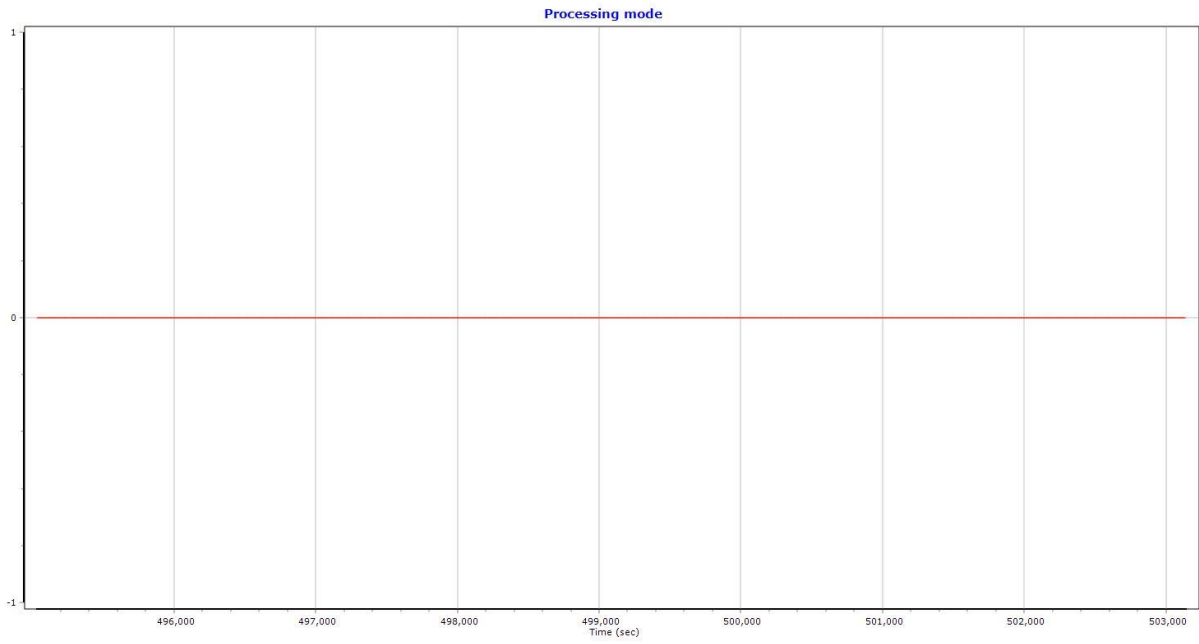
— Number of GPS Satellites — Number of GLONASS Satellites



Forward Reverse



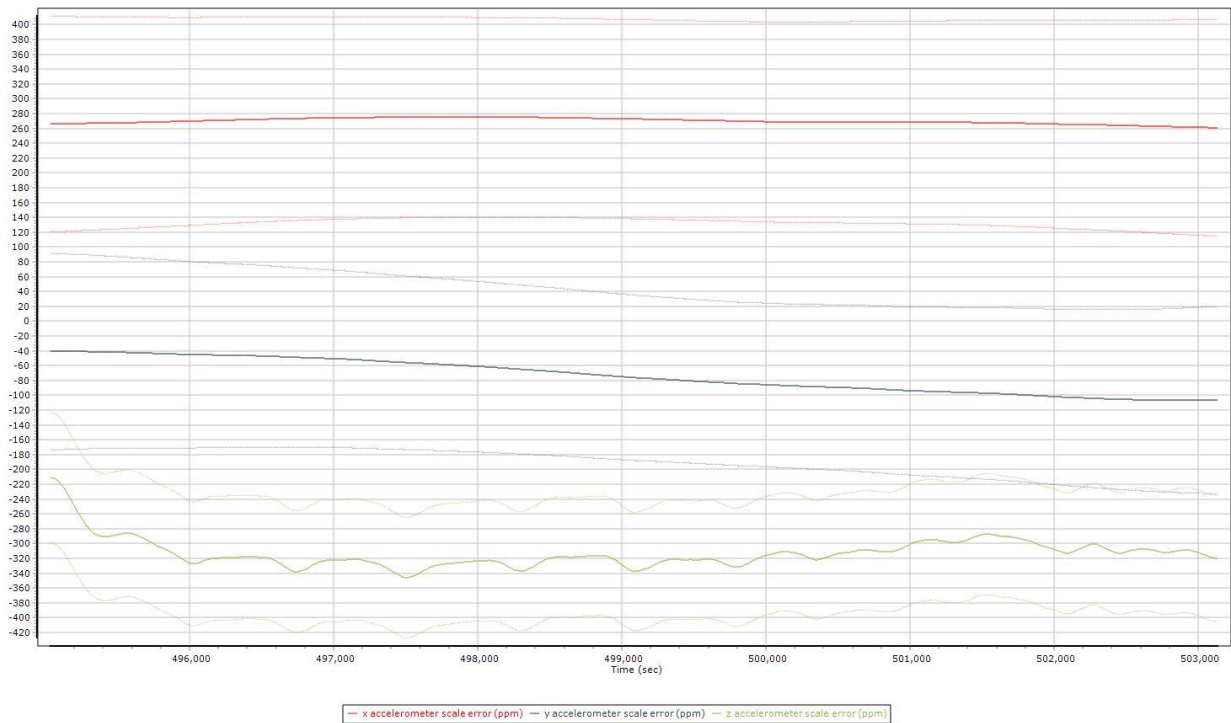
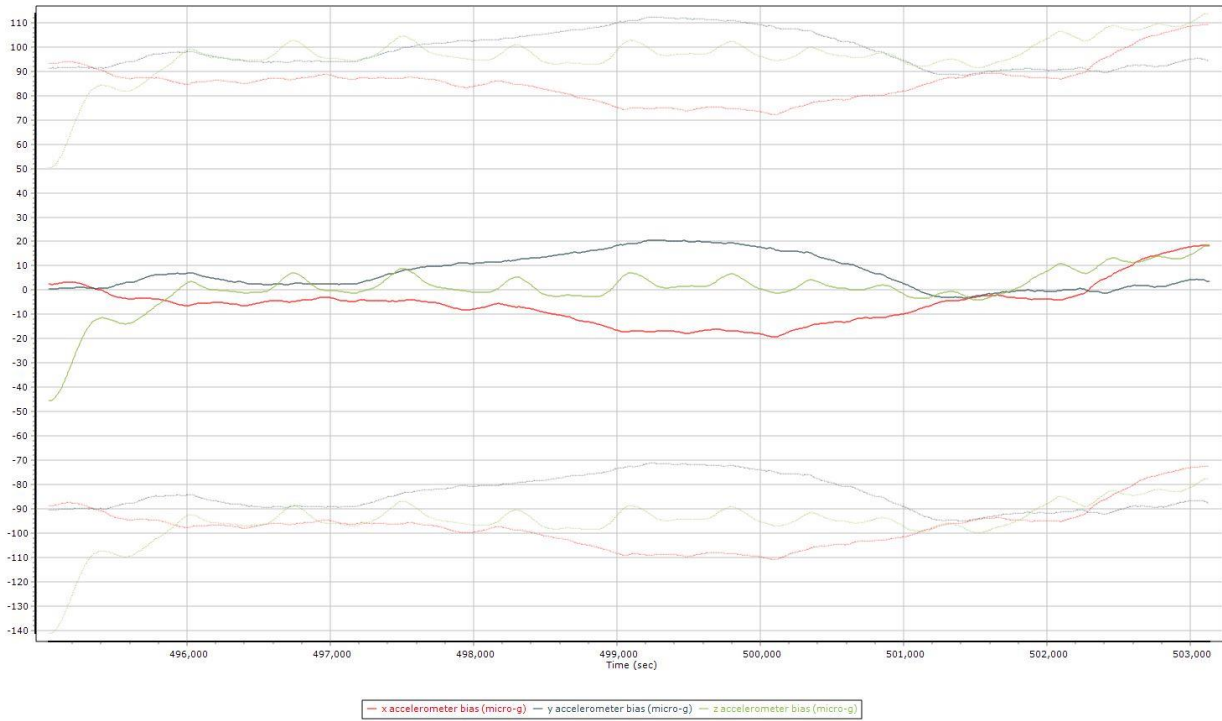
Forward Reverse

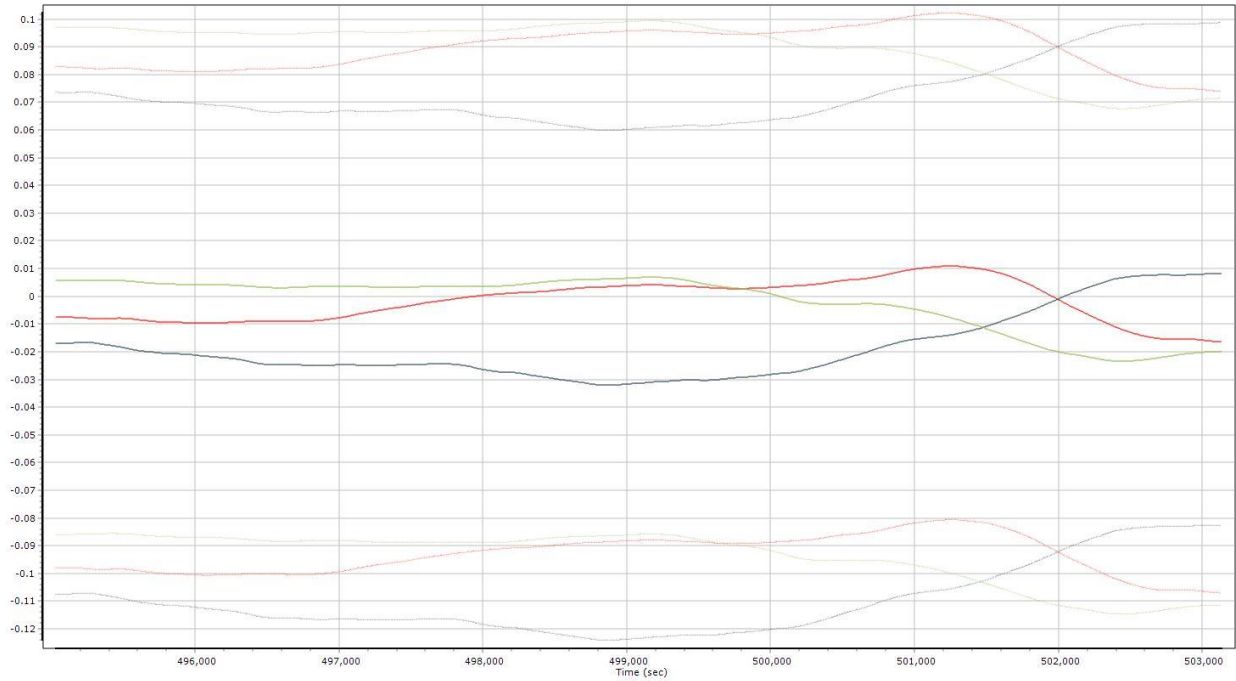


Forward Reverse

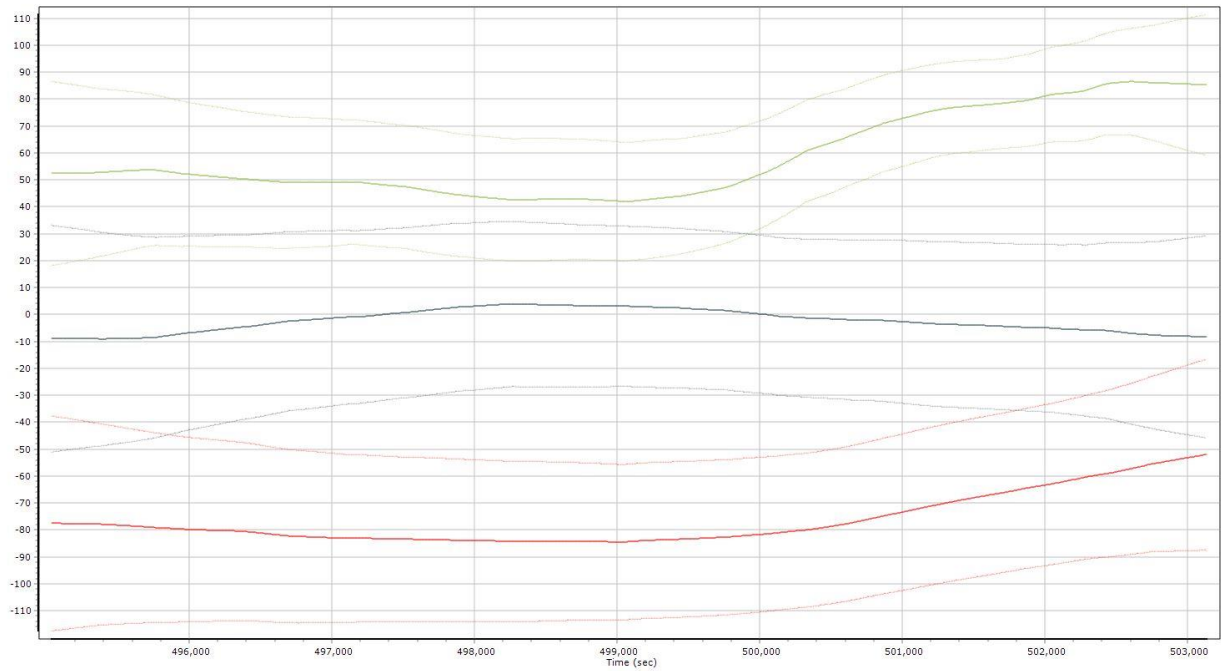
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors



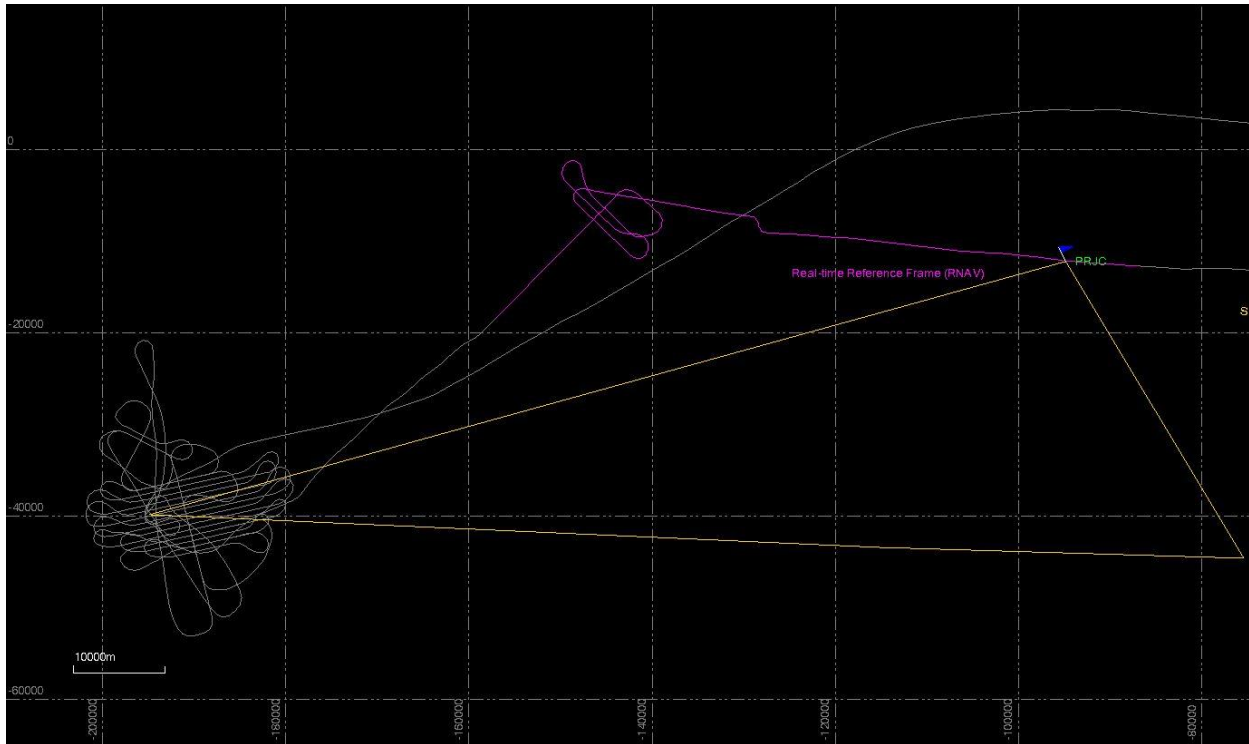


x gyro bias (deg/hr) y gyro bias (deg/hr) z gyro bias (deg/hr)



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

AZT18159B3



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

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

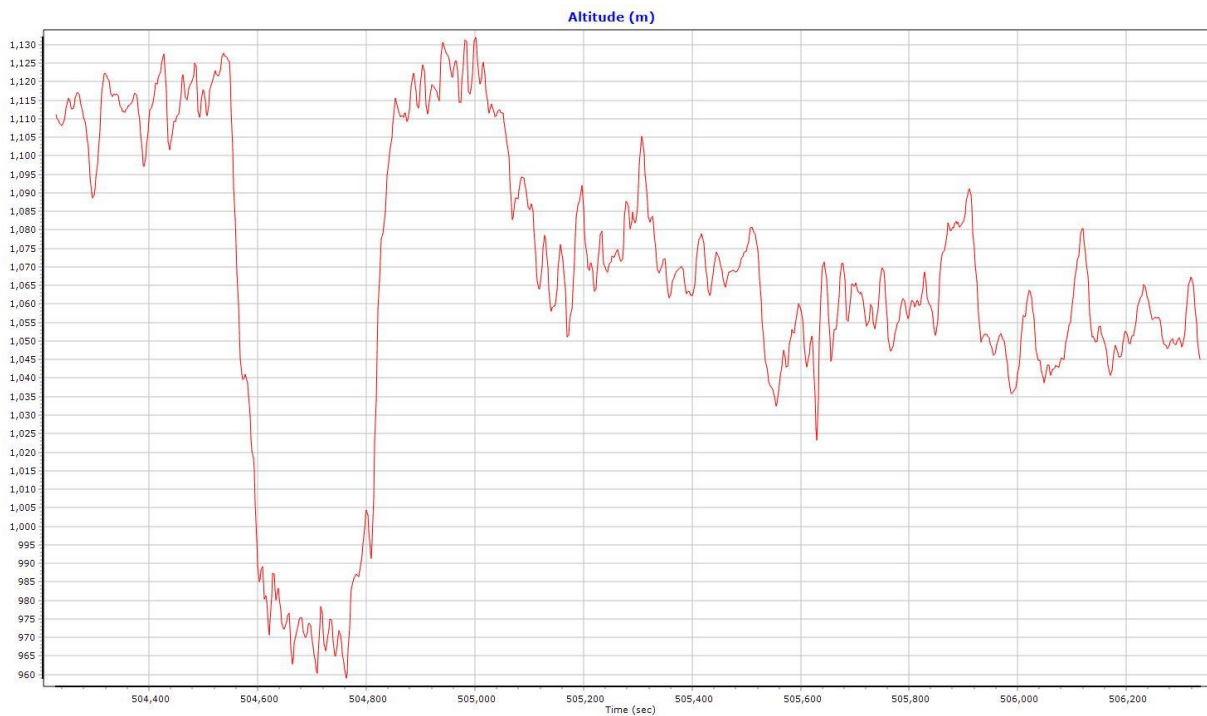
Start: 504227.689
End: 506338.185

Entire time interval
 Seconds of start week

UTC Offset: 18.000

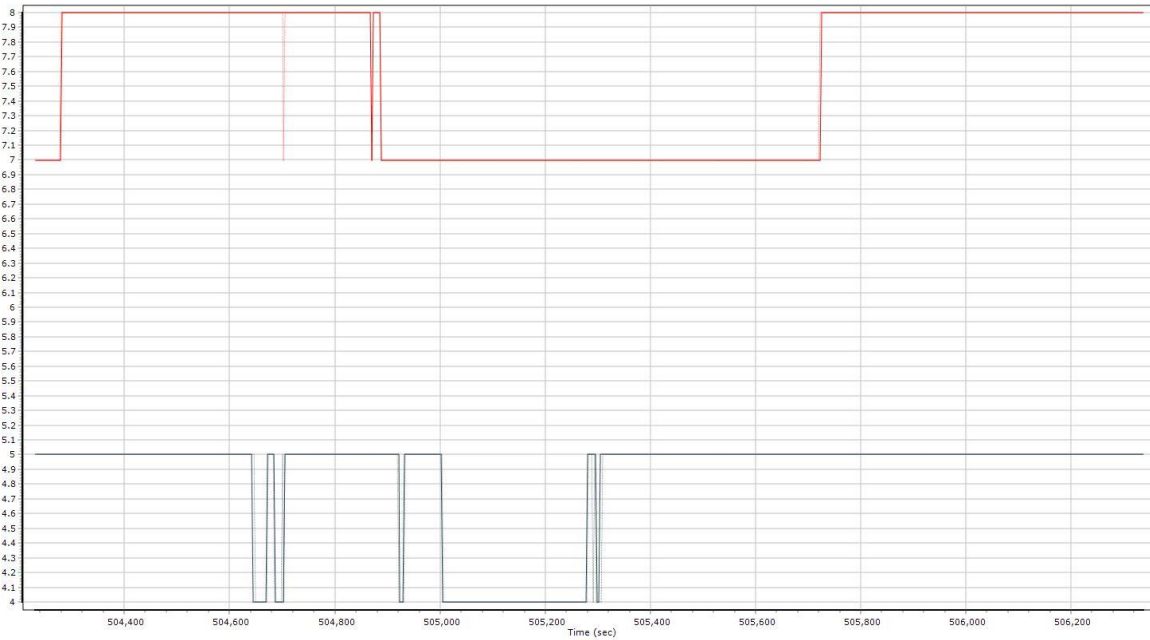
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel

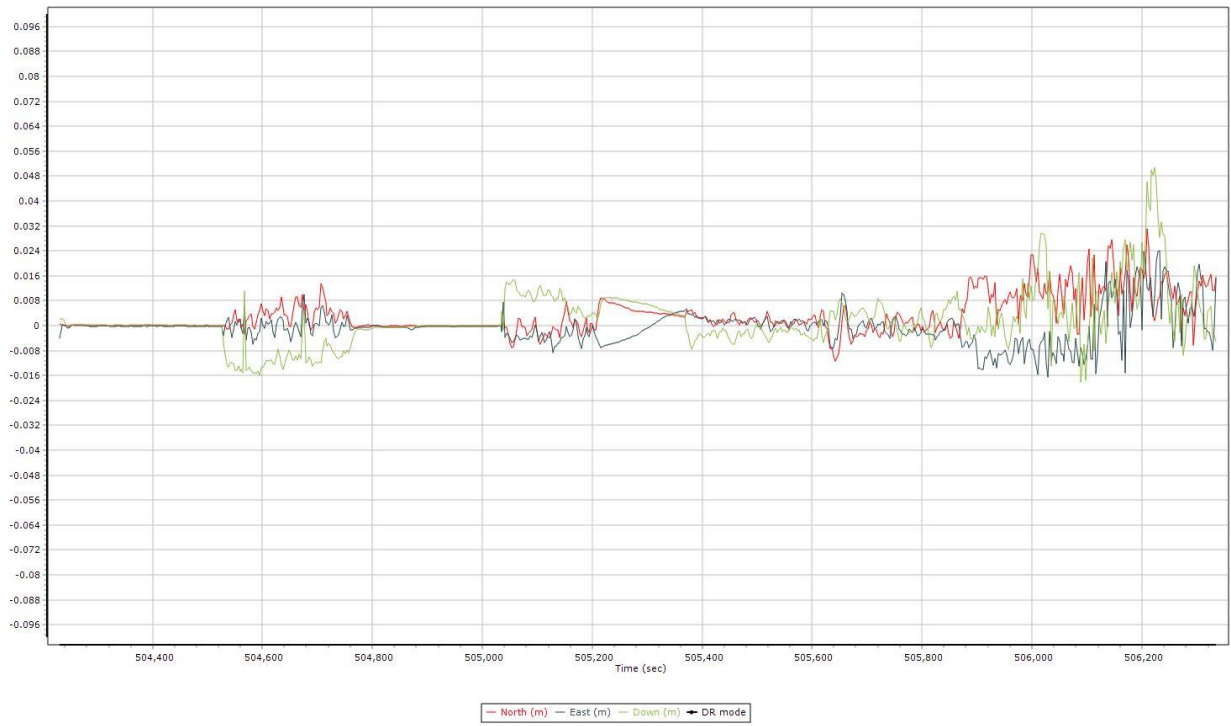
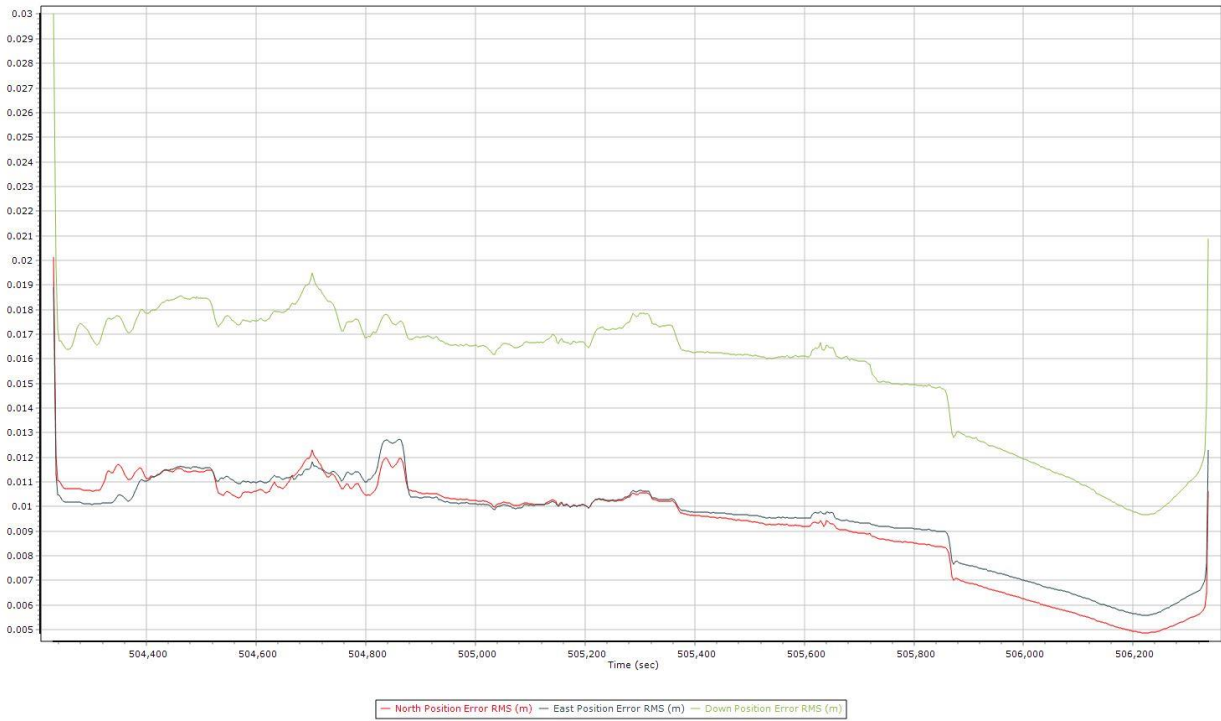


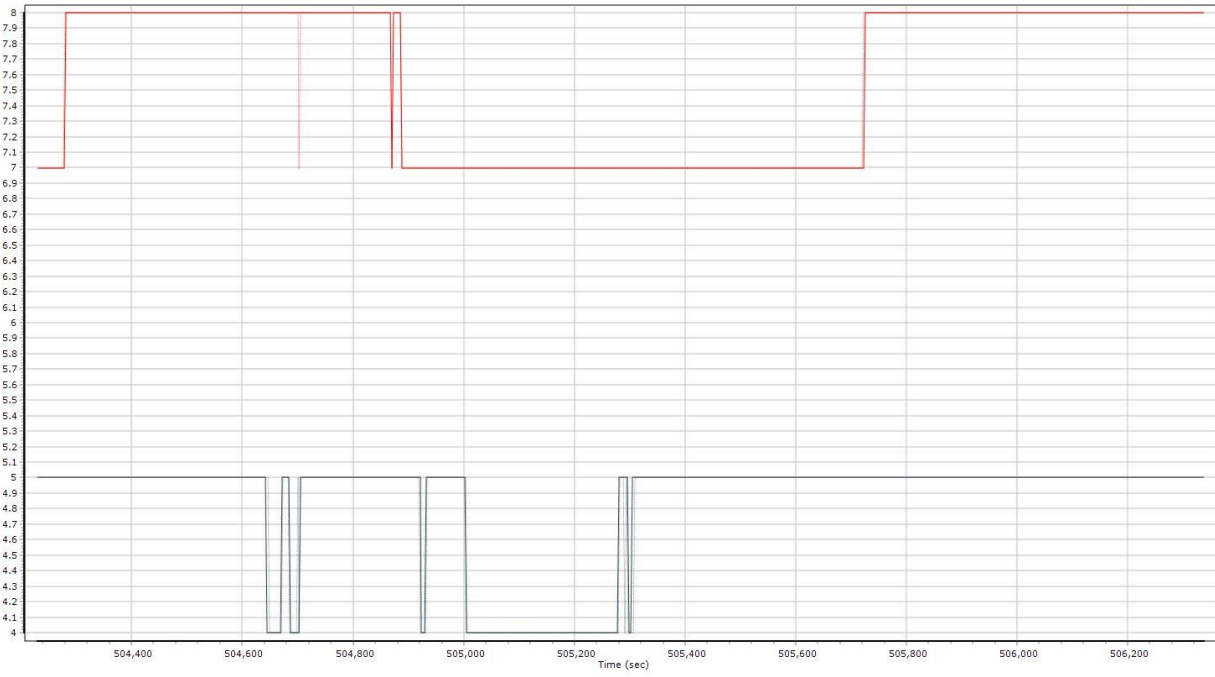


— Roll (deg) — Pitch (deg)

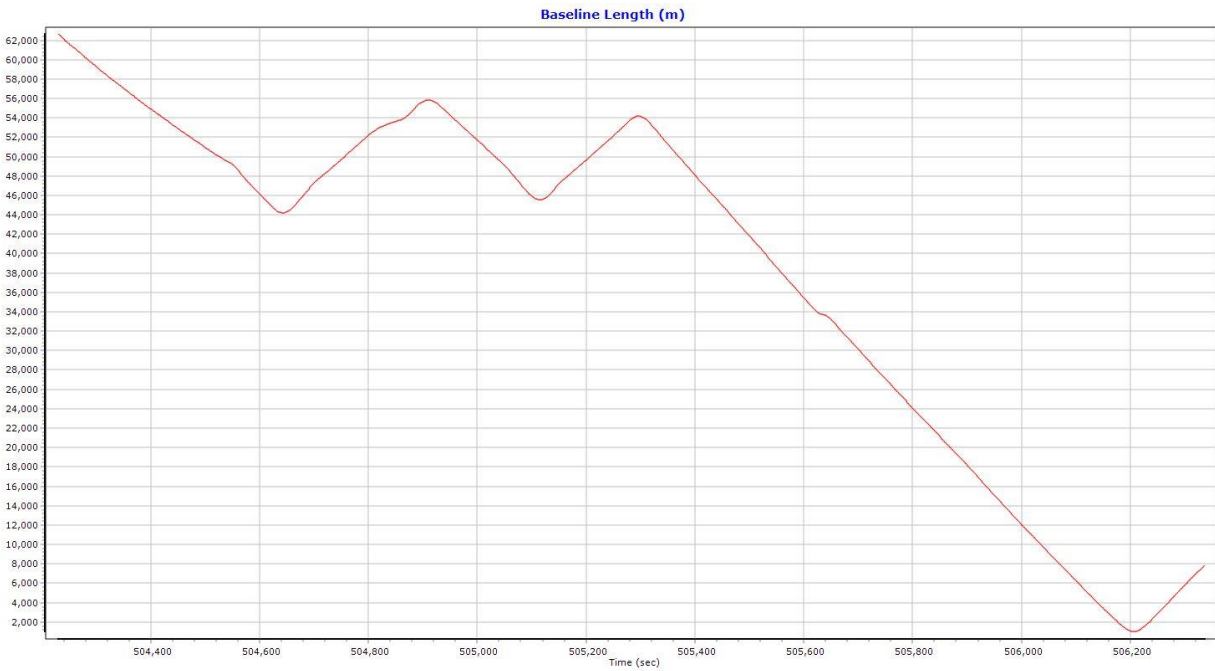


— Number of GPS Satellites — Number of GLONASS Satellites

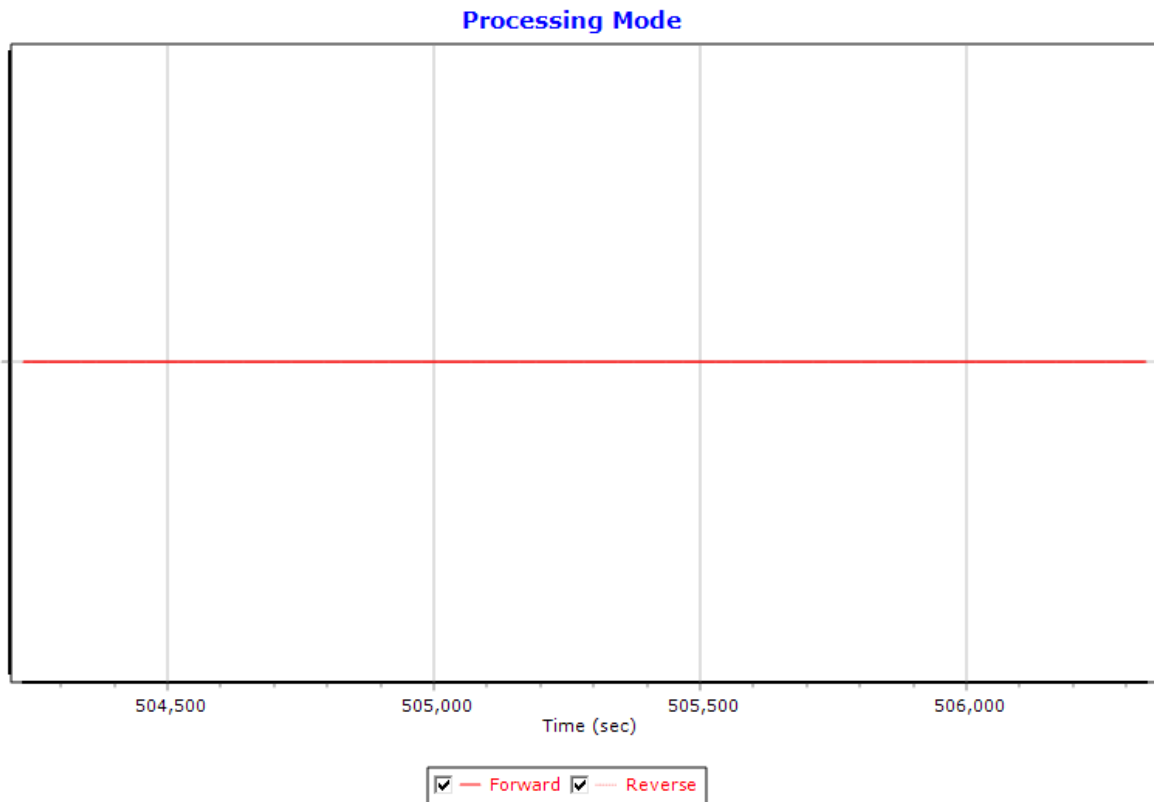
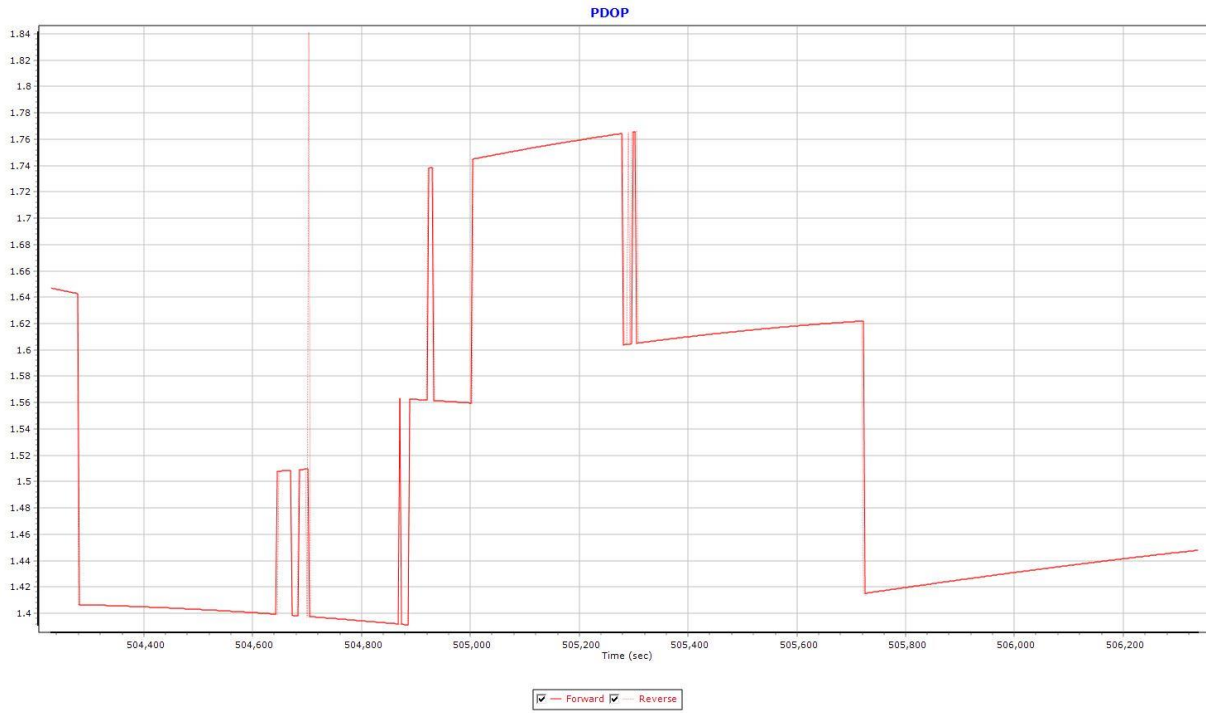




— Number of GPS Satellites — Number of GLONASS Satellites

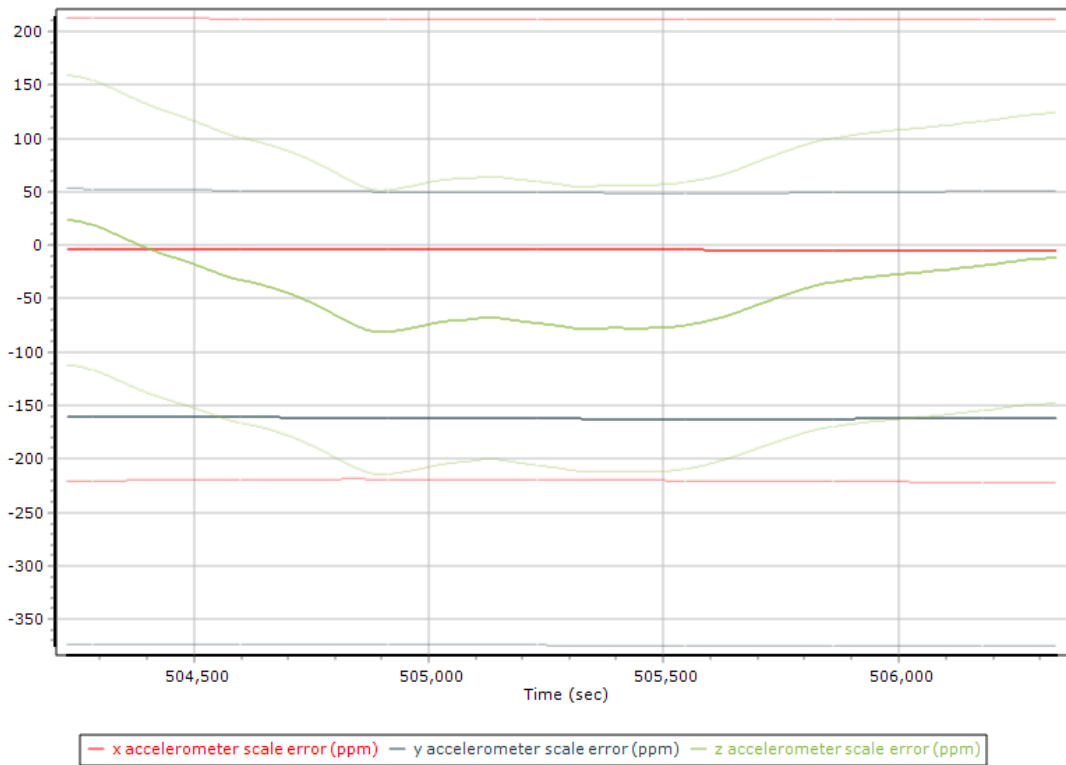
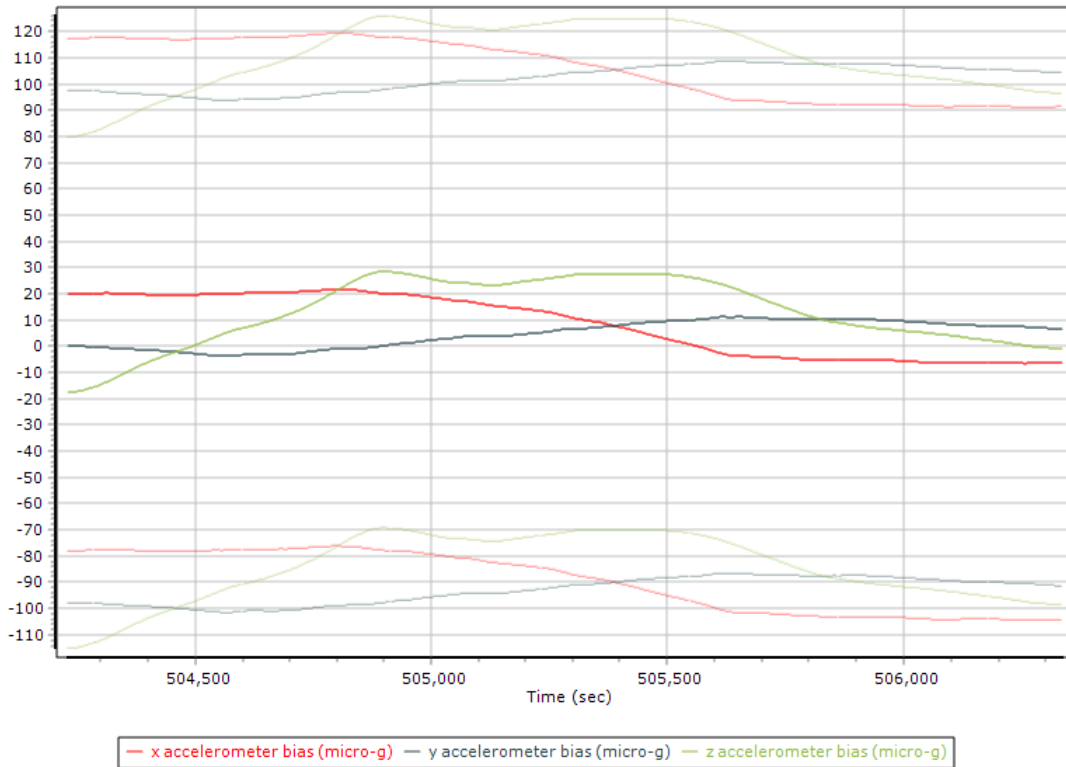


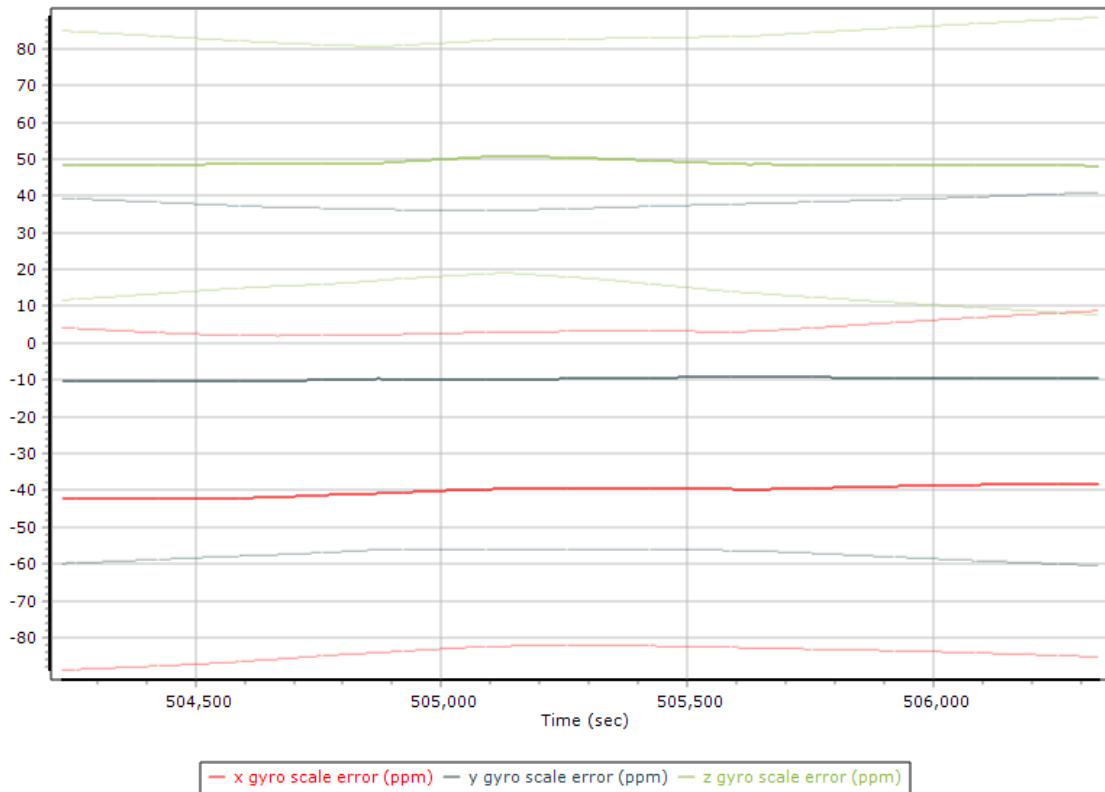
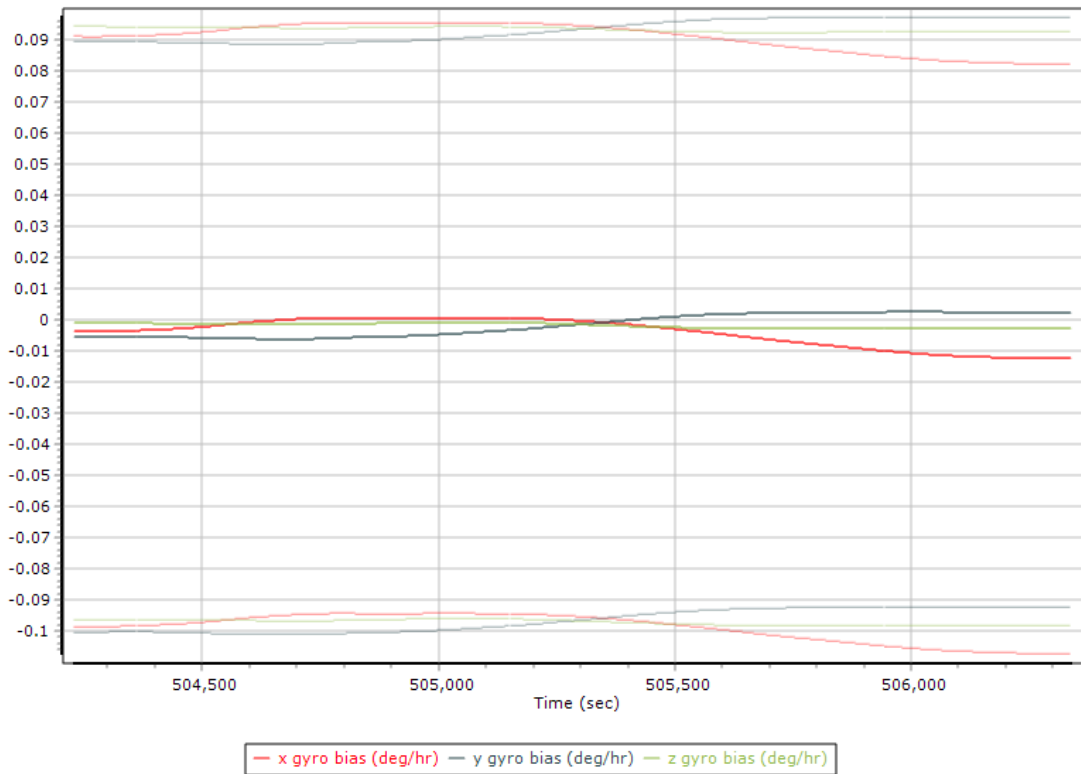
Forward Reverse



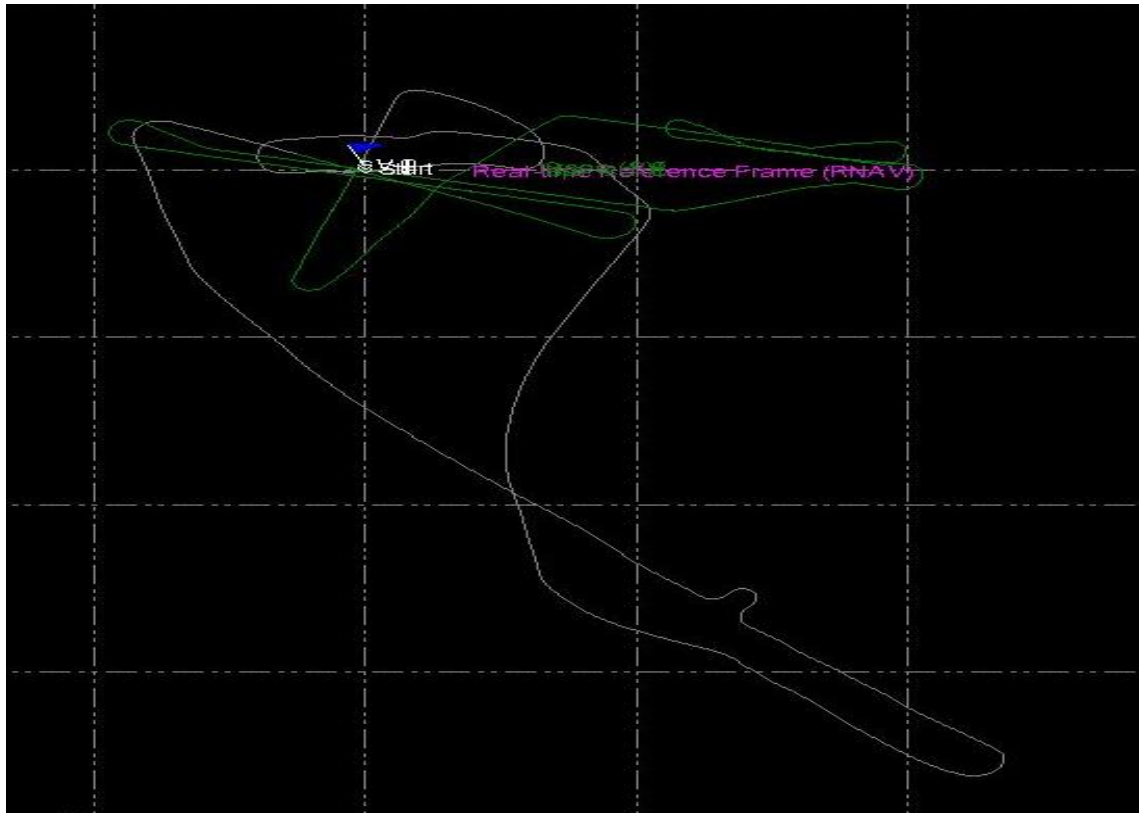
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





45A18234A



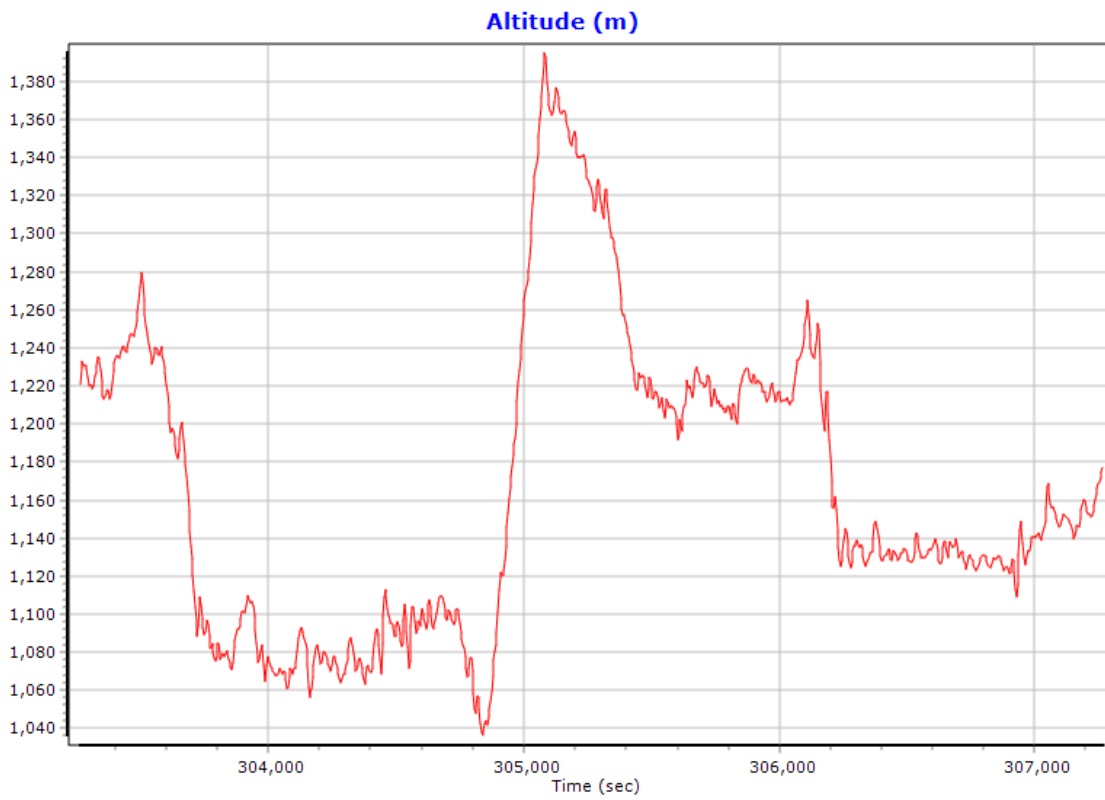
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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		

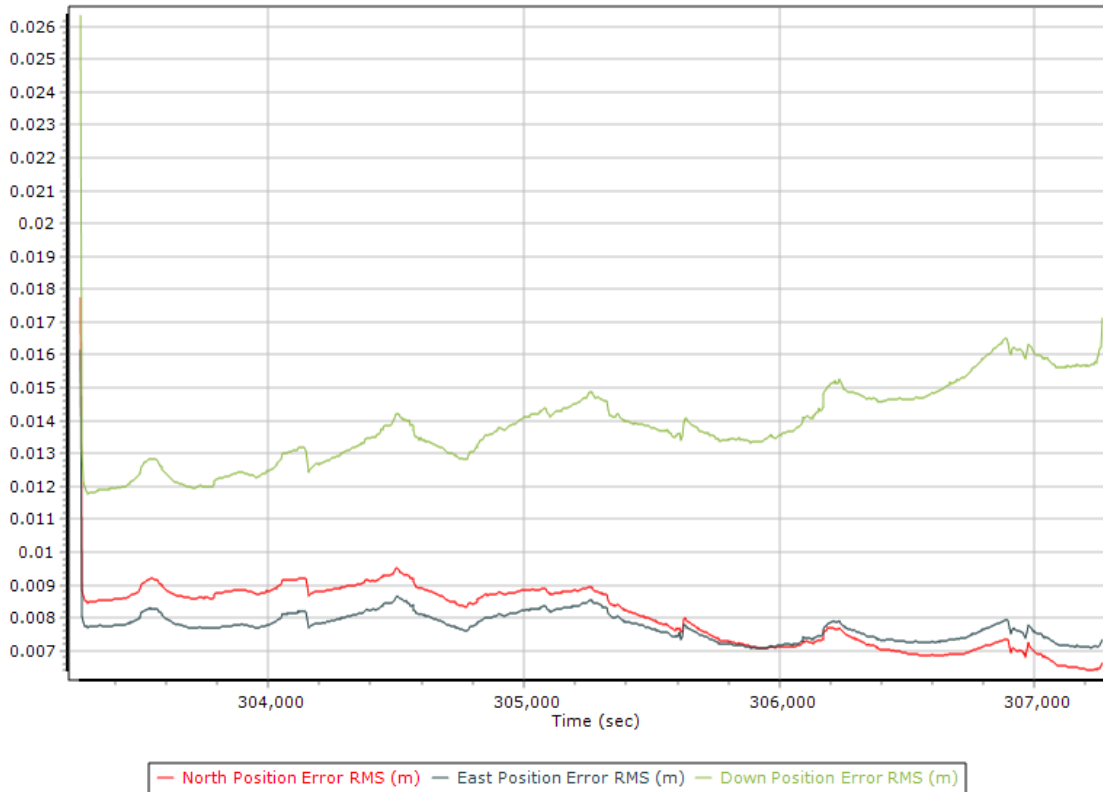
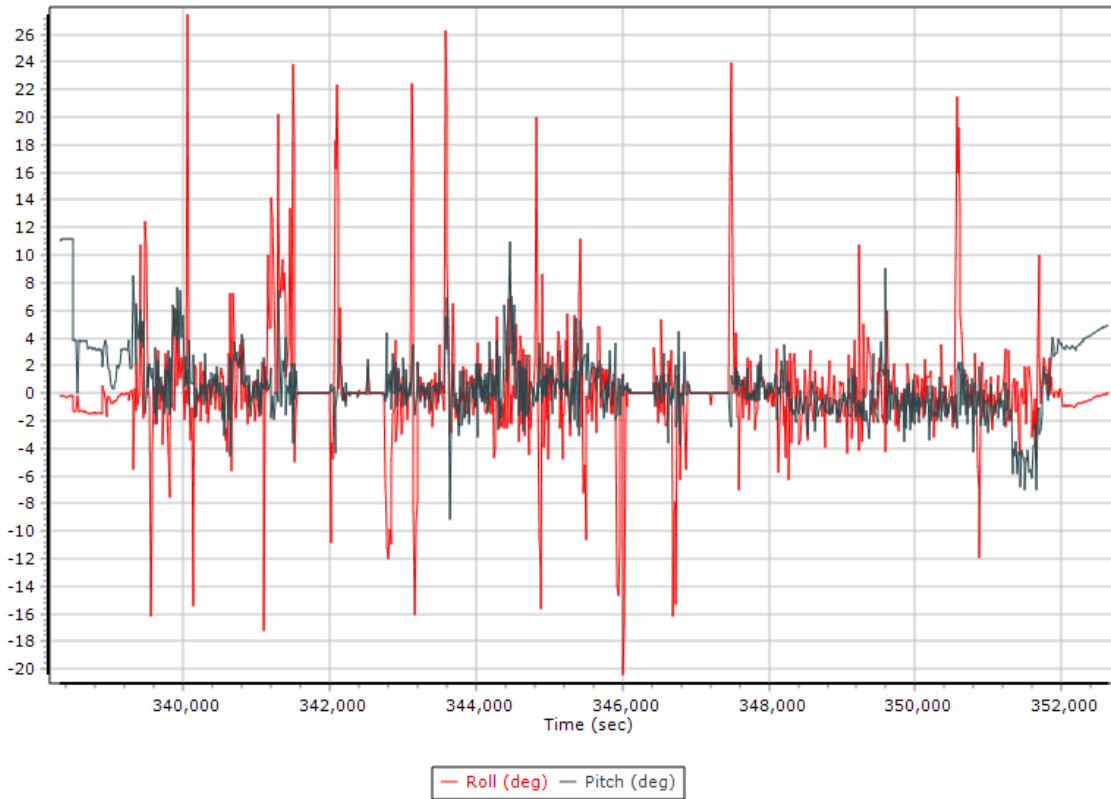
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

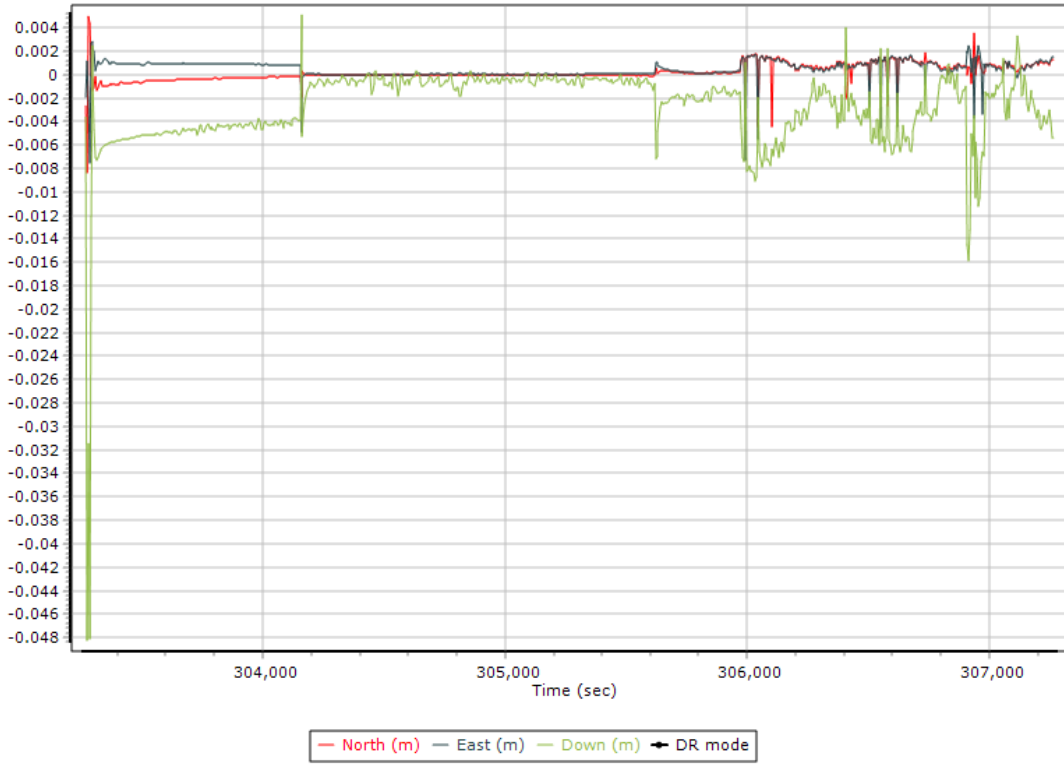
Timing

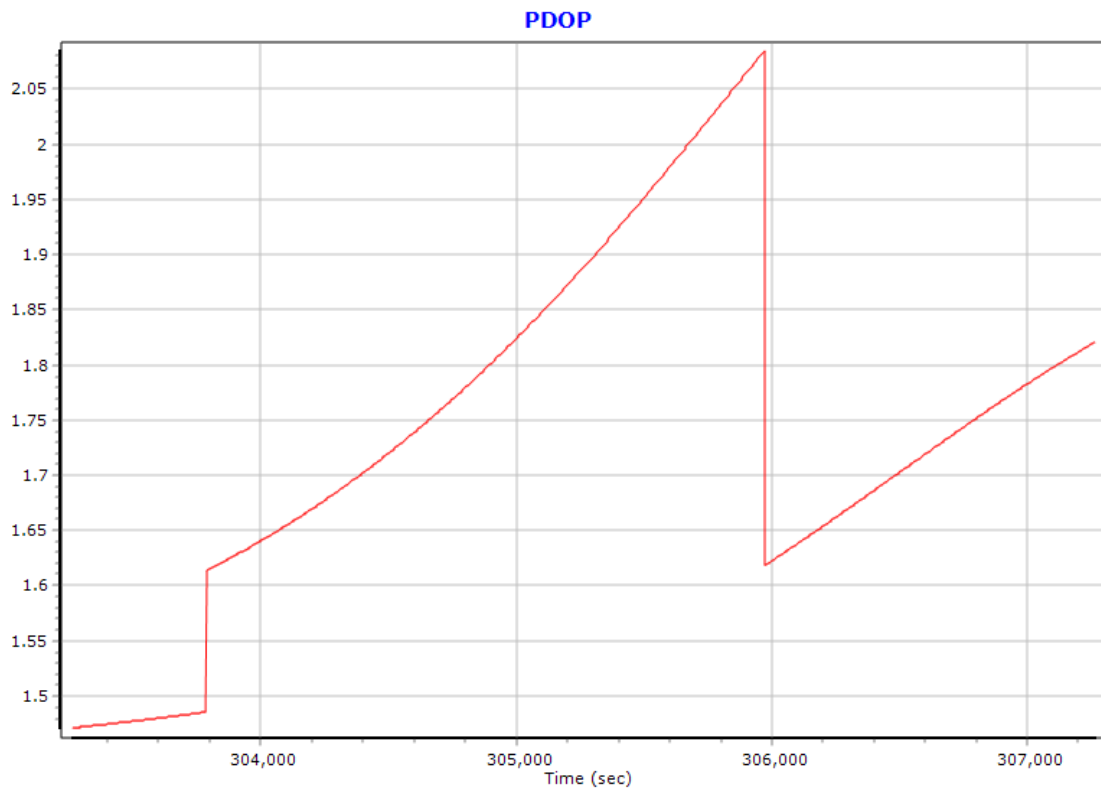
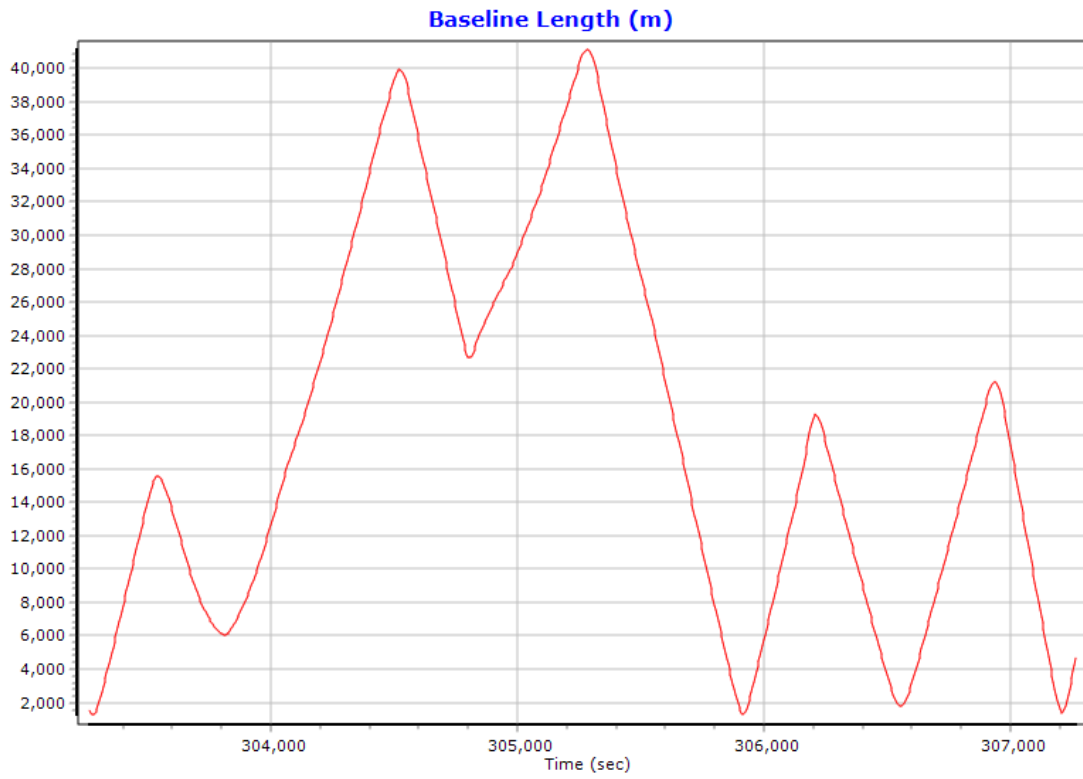
Start	303261.932	Data	Incr. (sec)
End	307272.703	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset 18.000

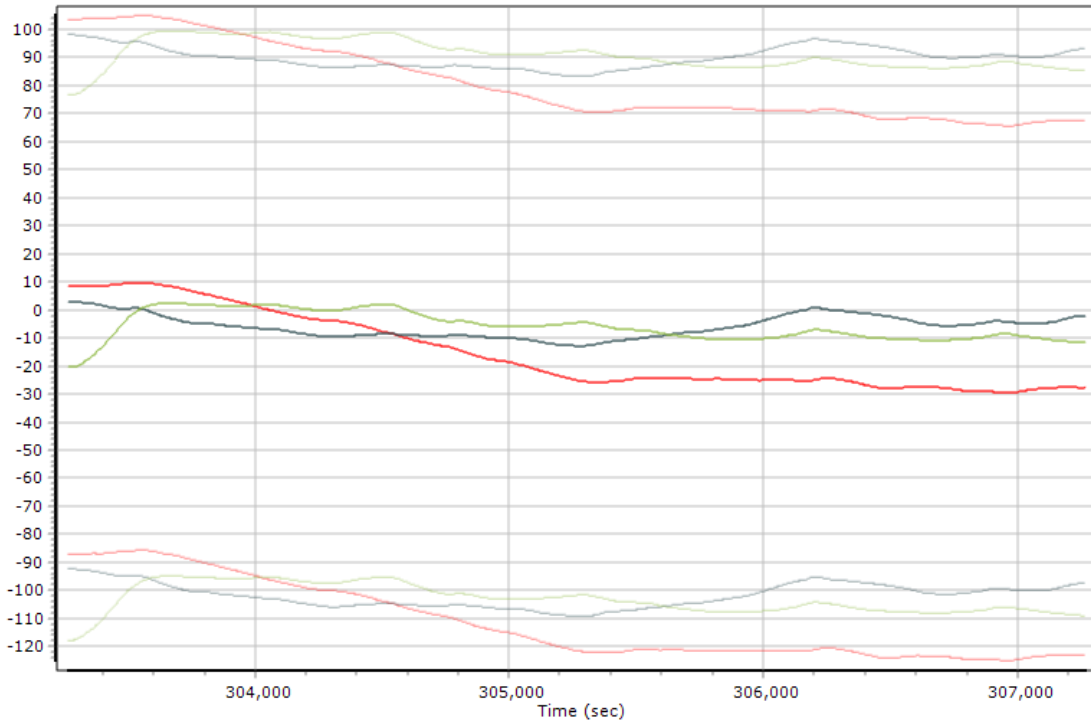




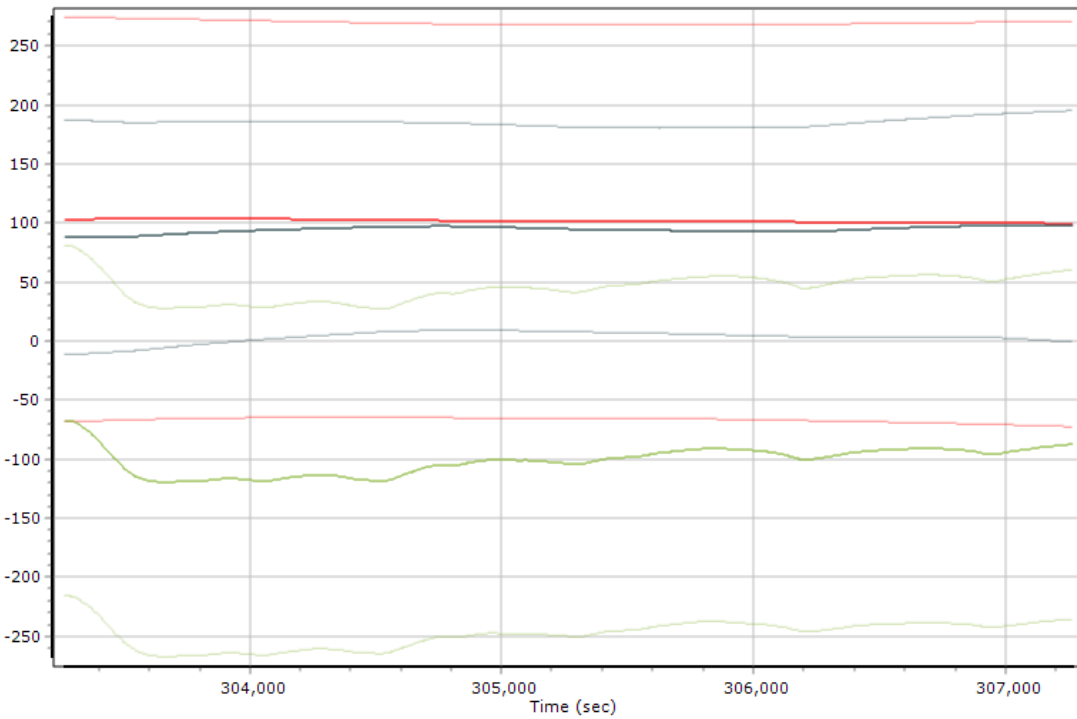




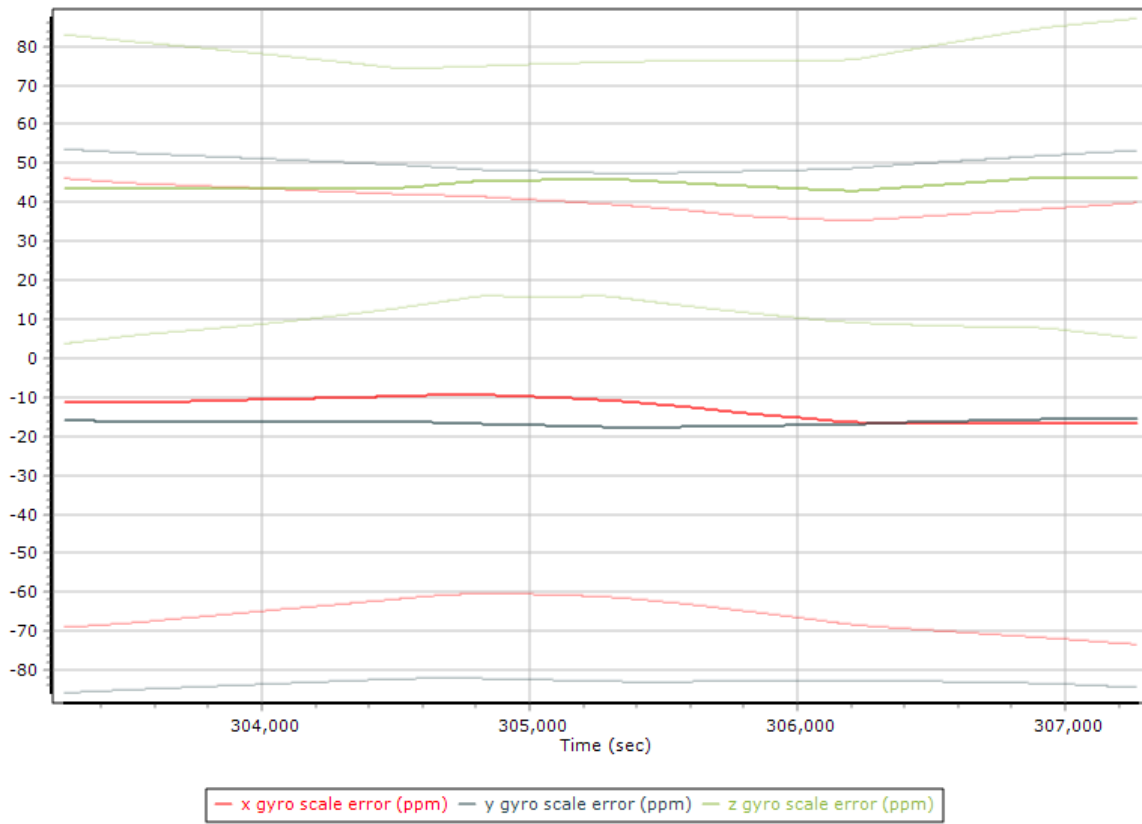
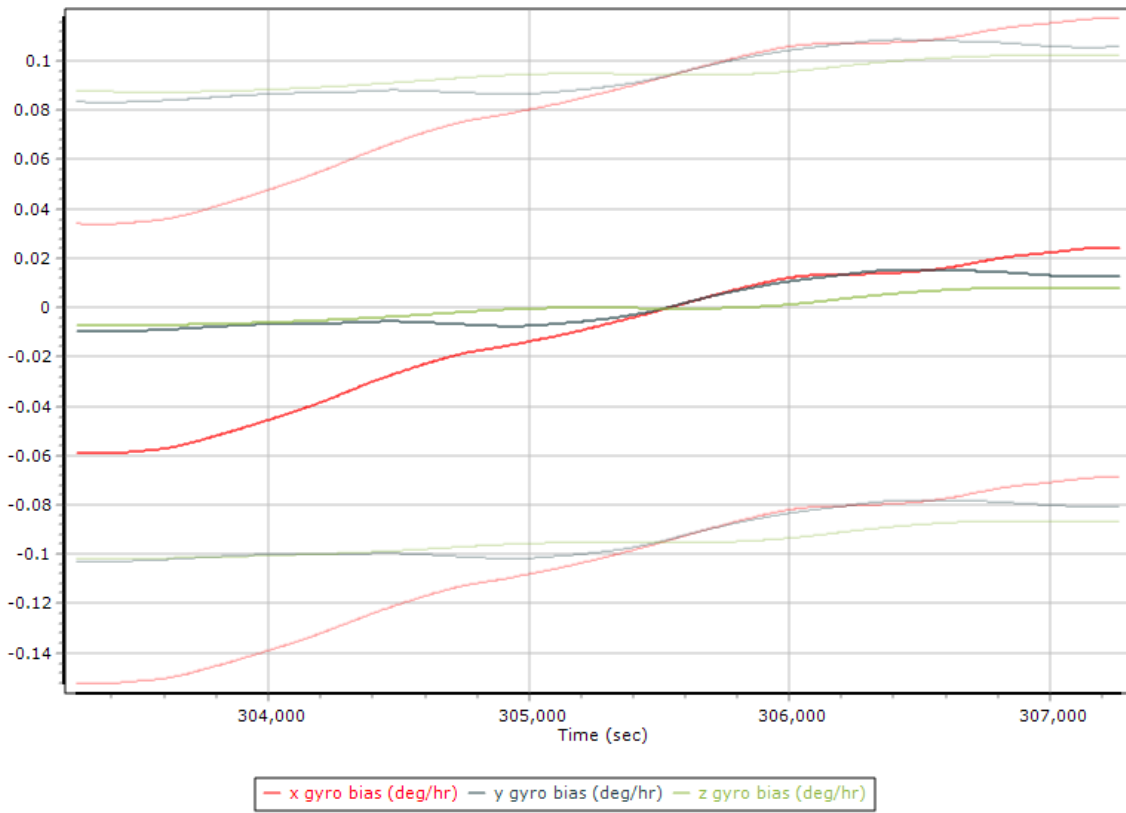
Sensor Errors



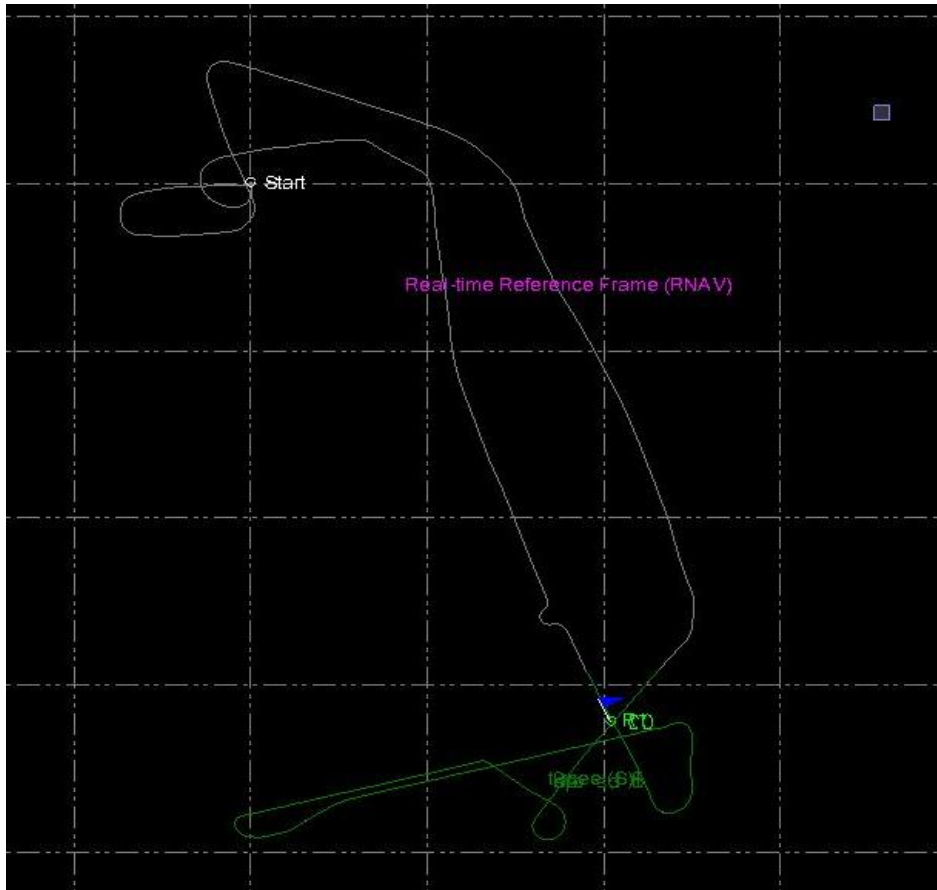
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



45A18238A



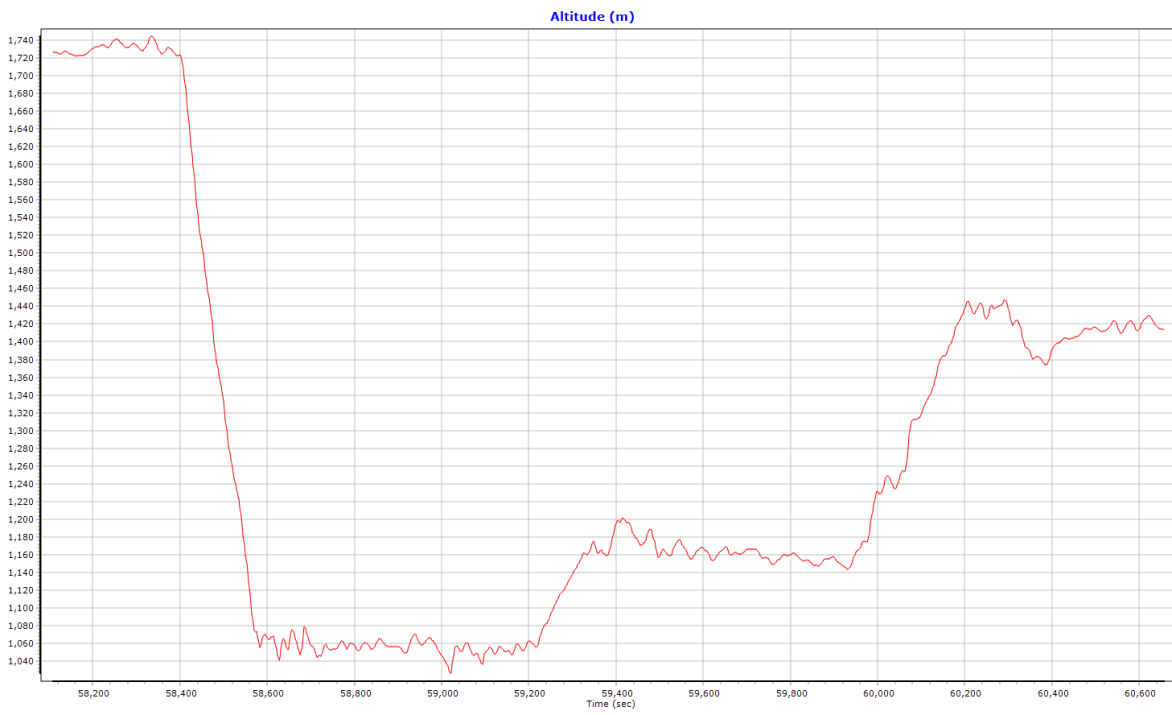
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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="3cm"/>		
	<3cm 10cm 50cm 1m 10m		

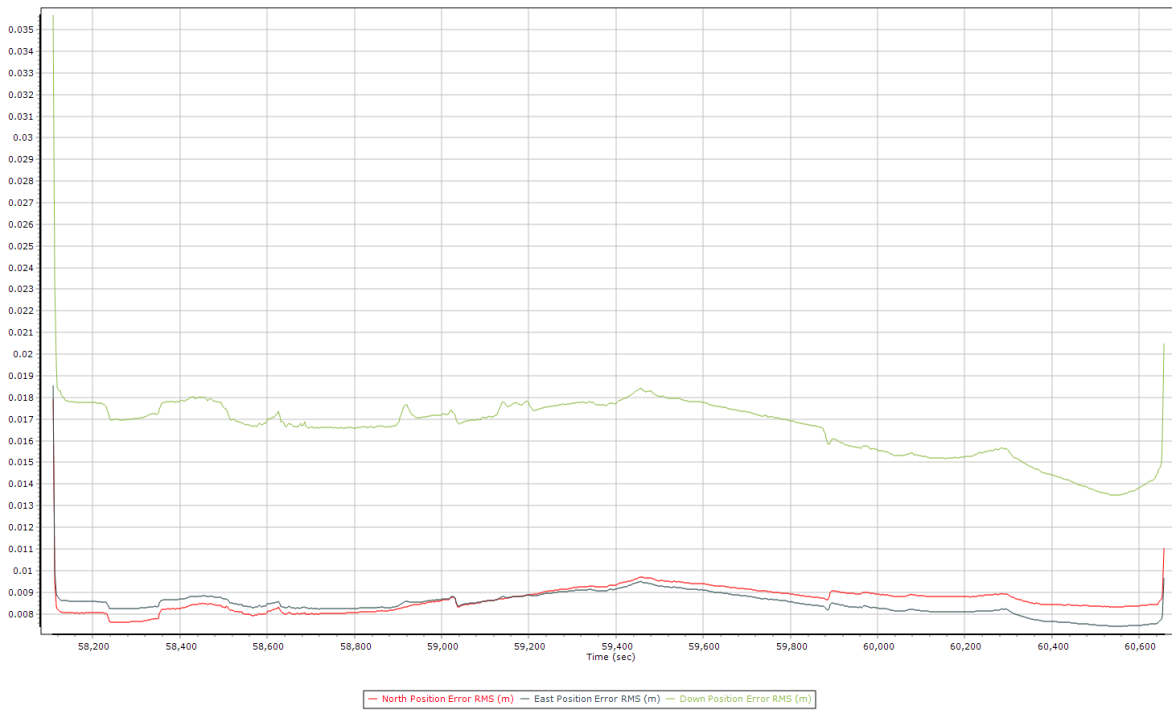
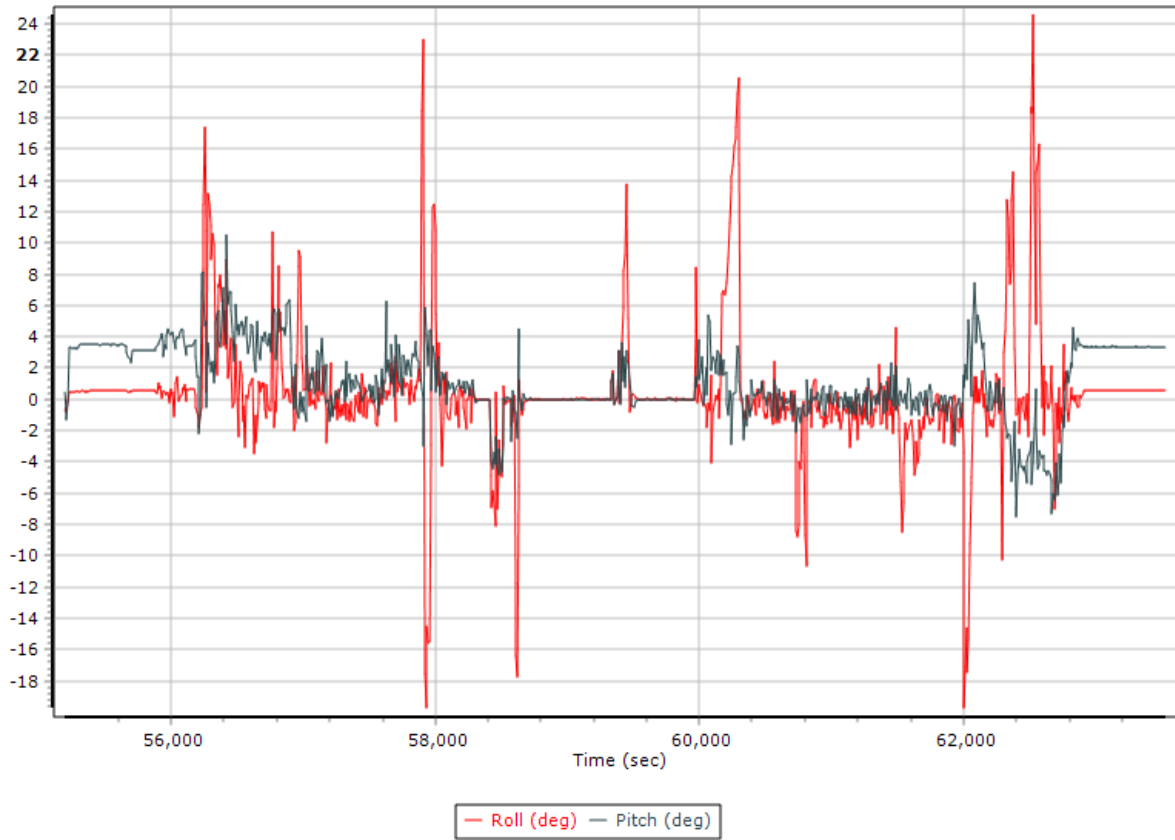
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

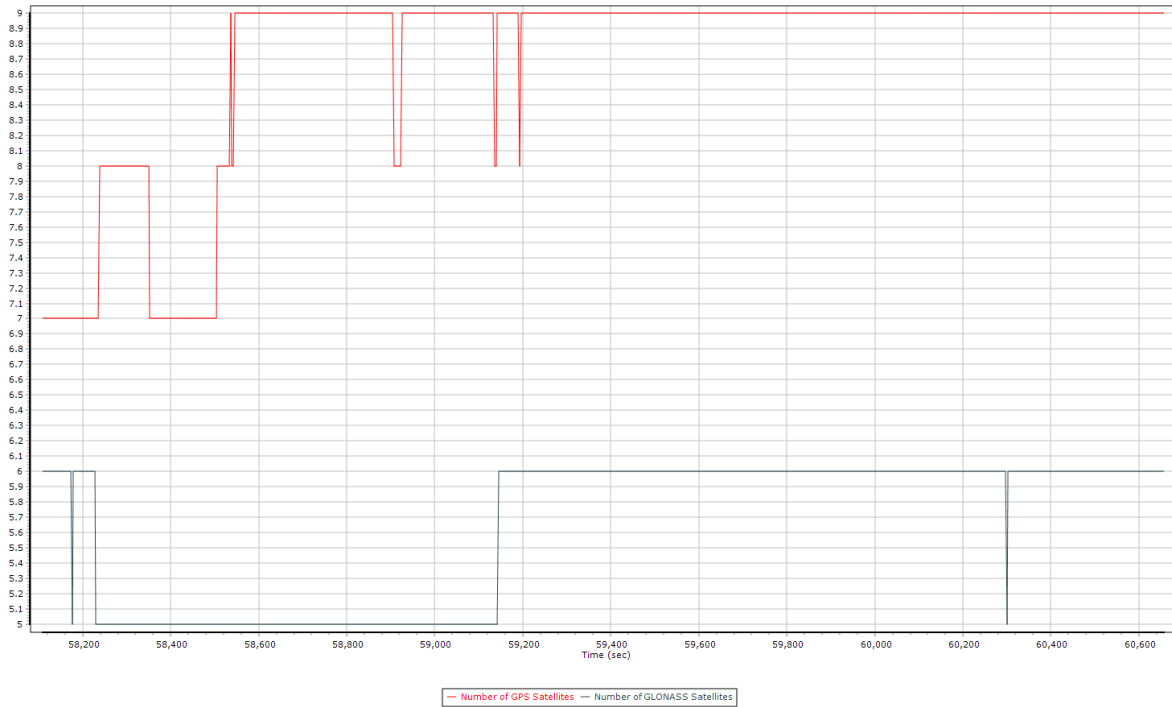
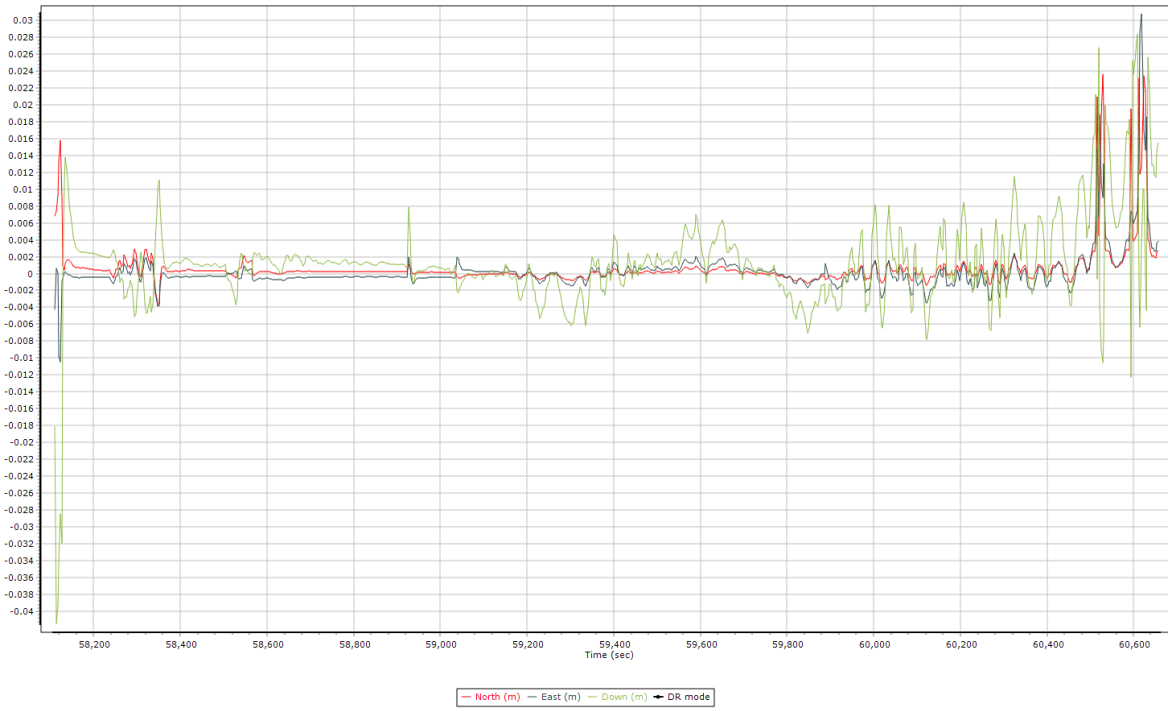
Timing

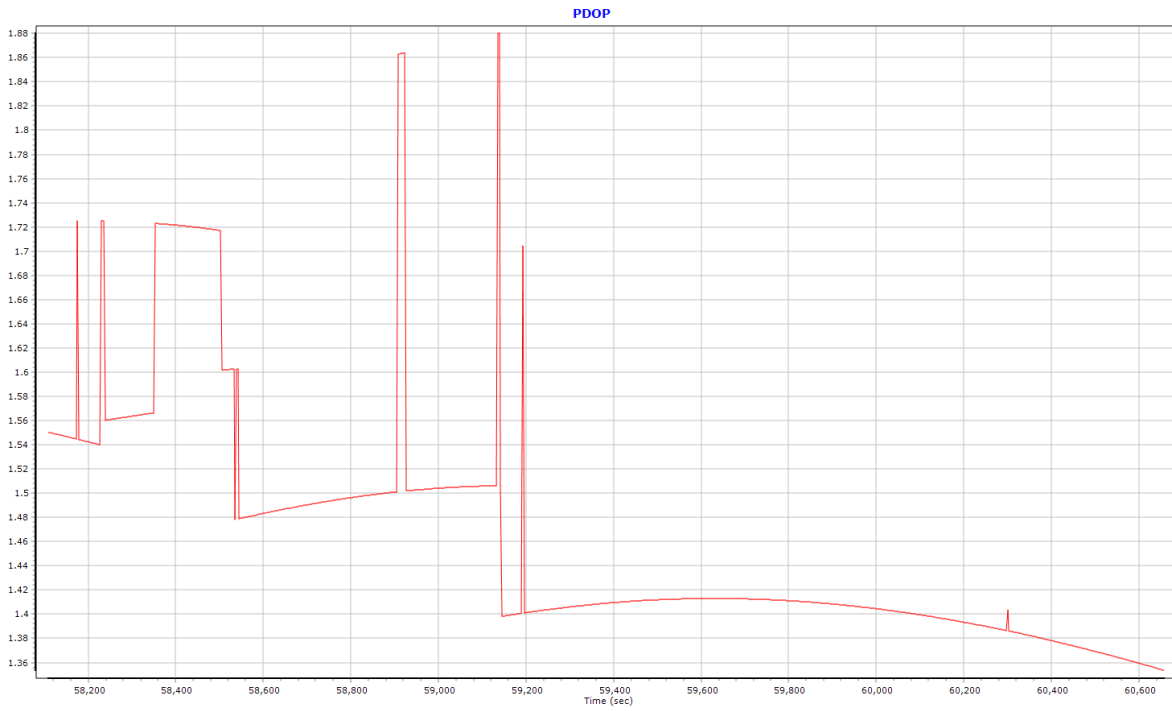
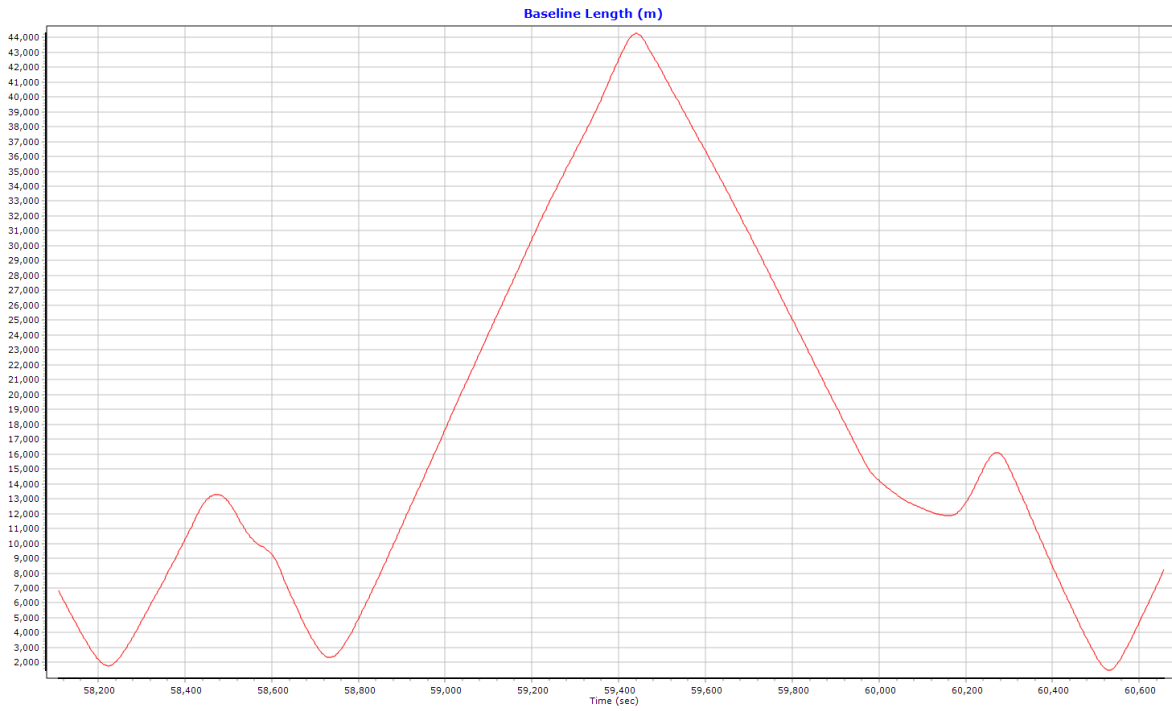
Start	58106.719	Data	Incr. (sec)
End	60659.215	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

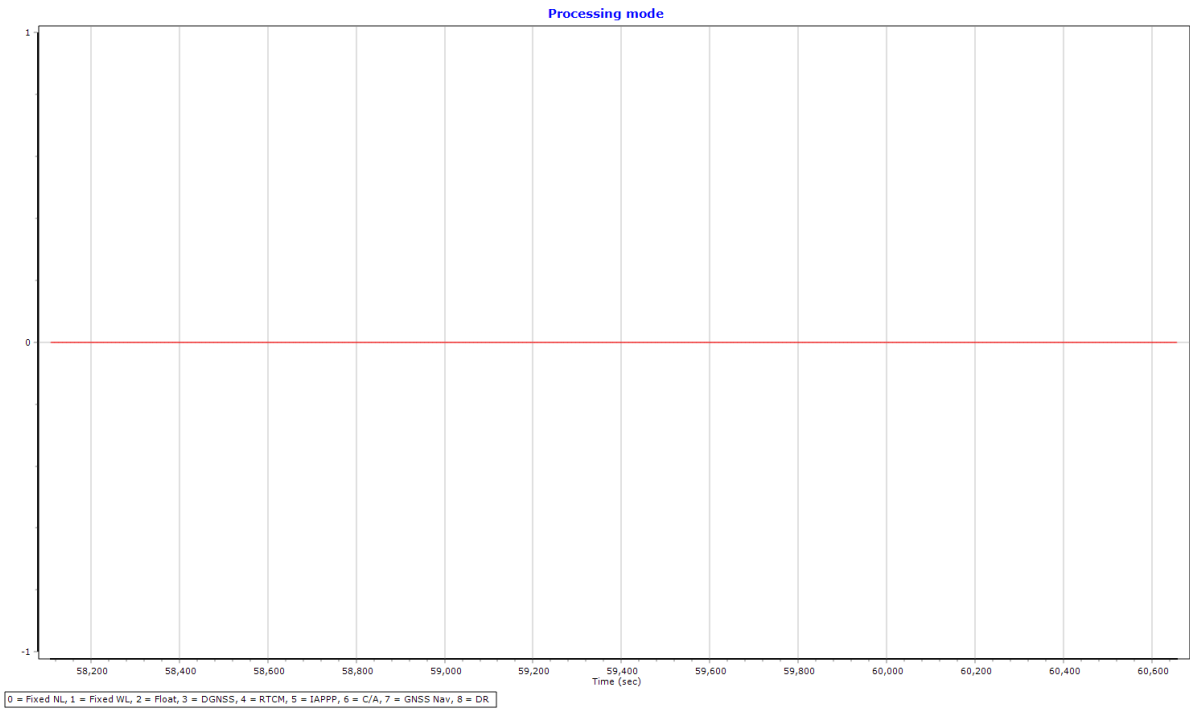
UTC Offset



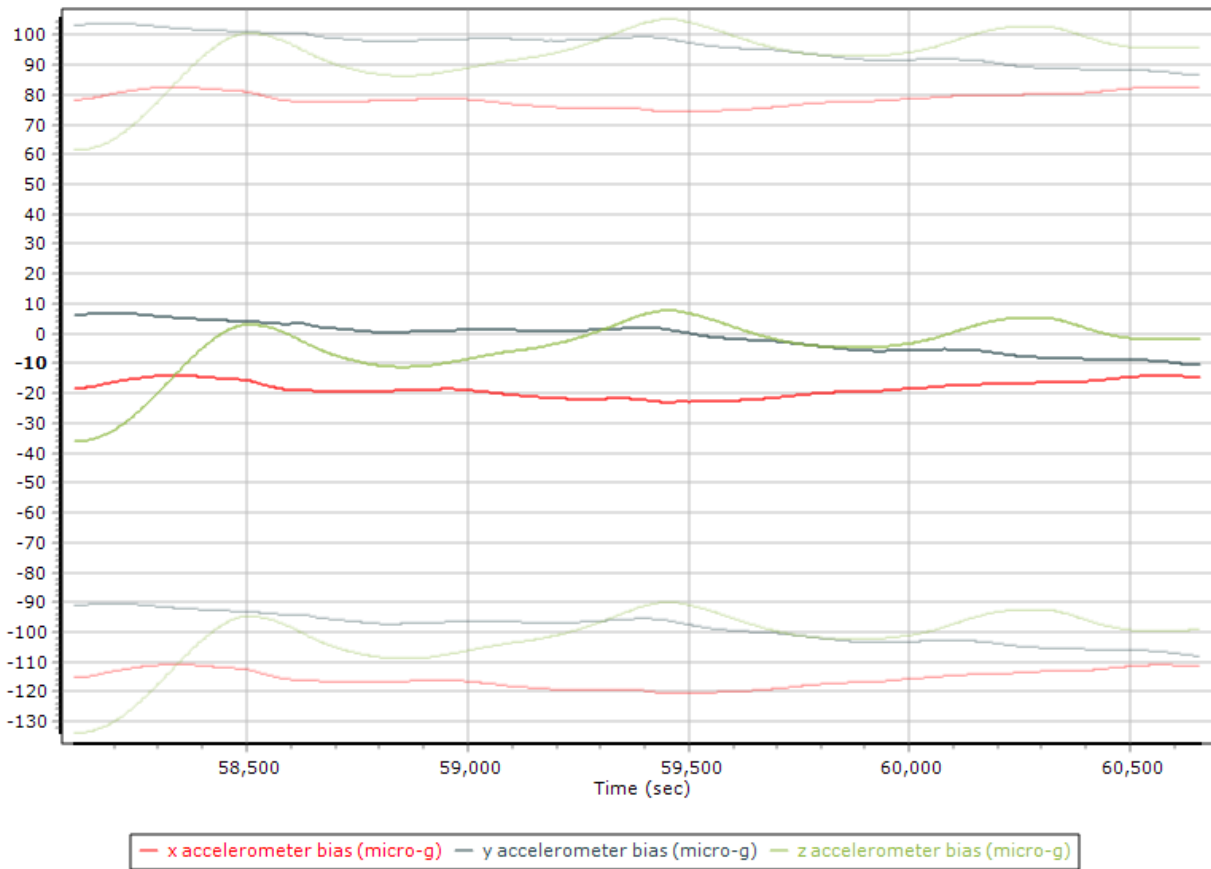


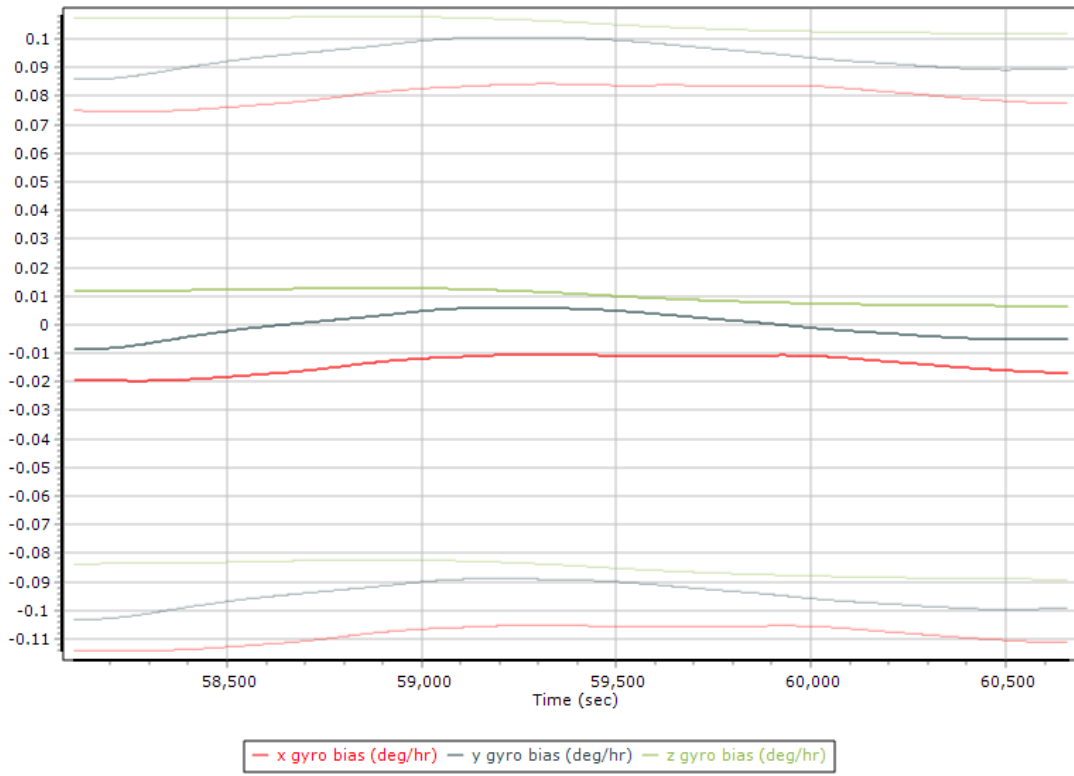
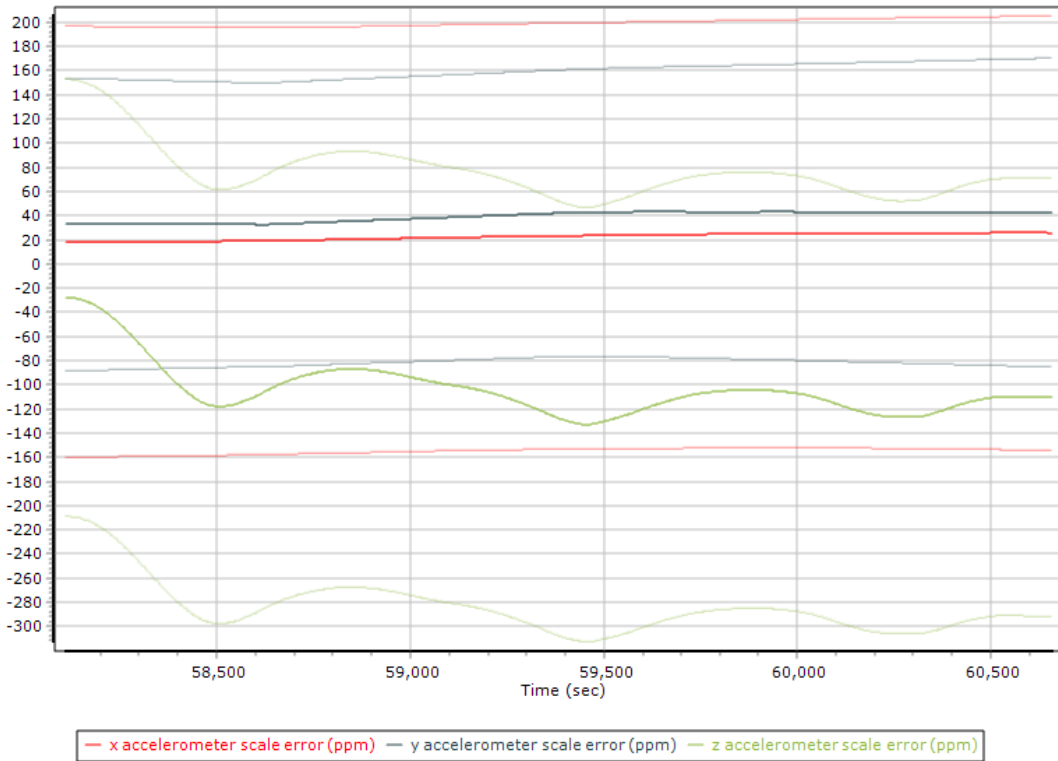


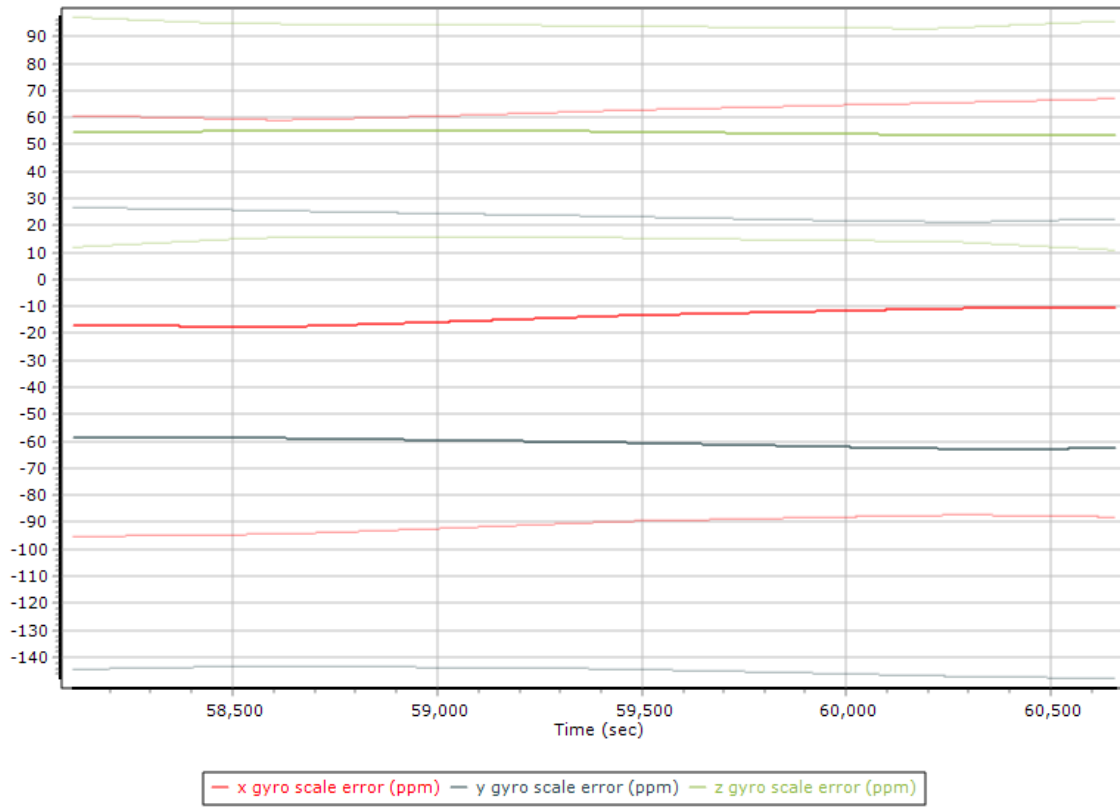




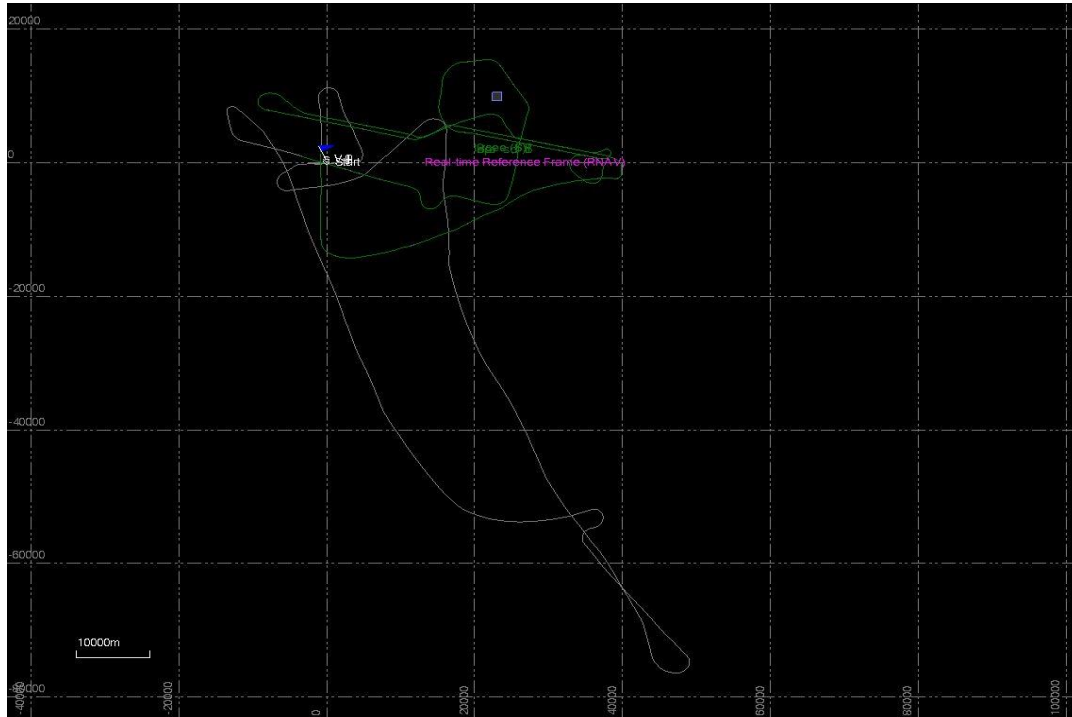
Sensor Errors







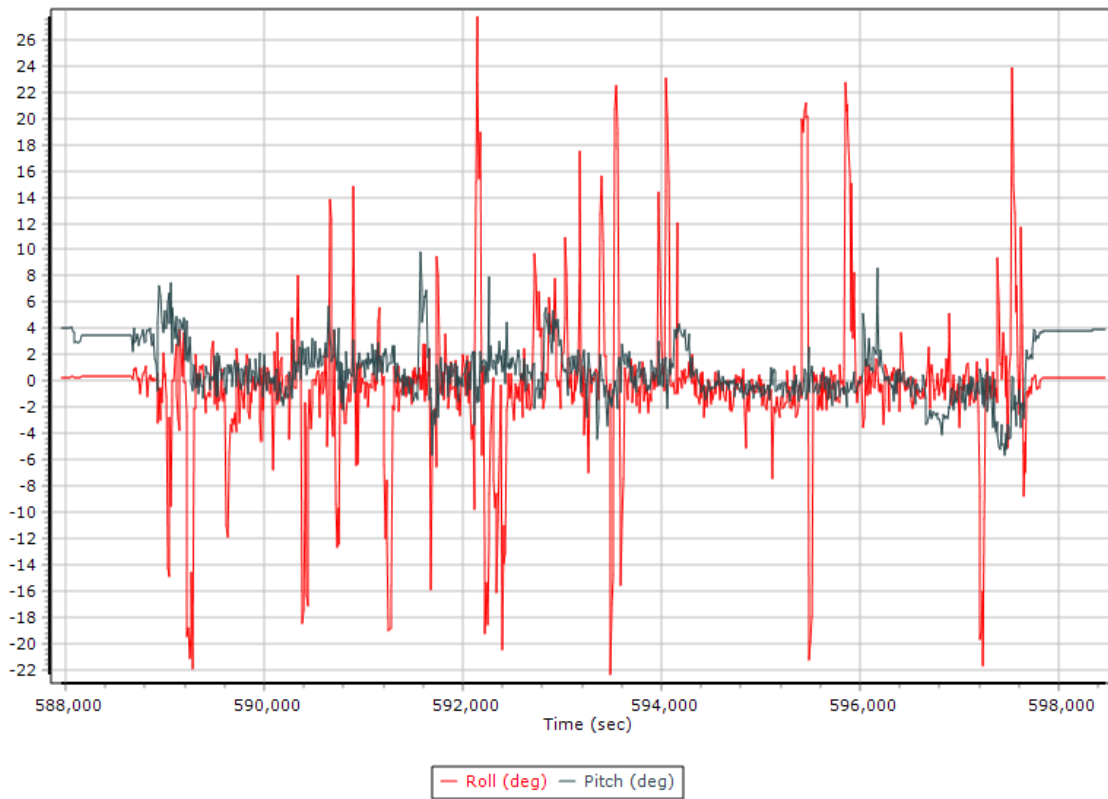
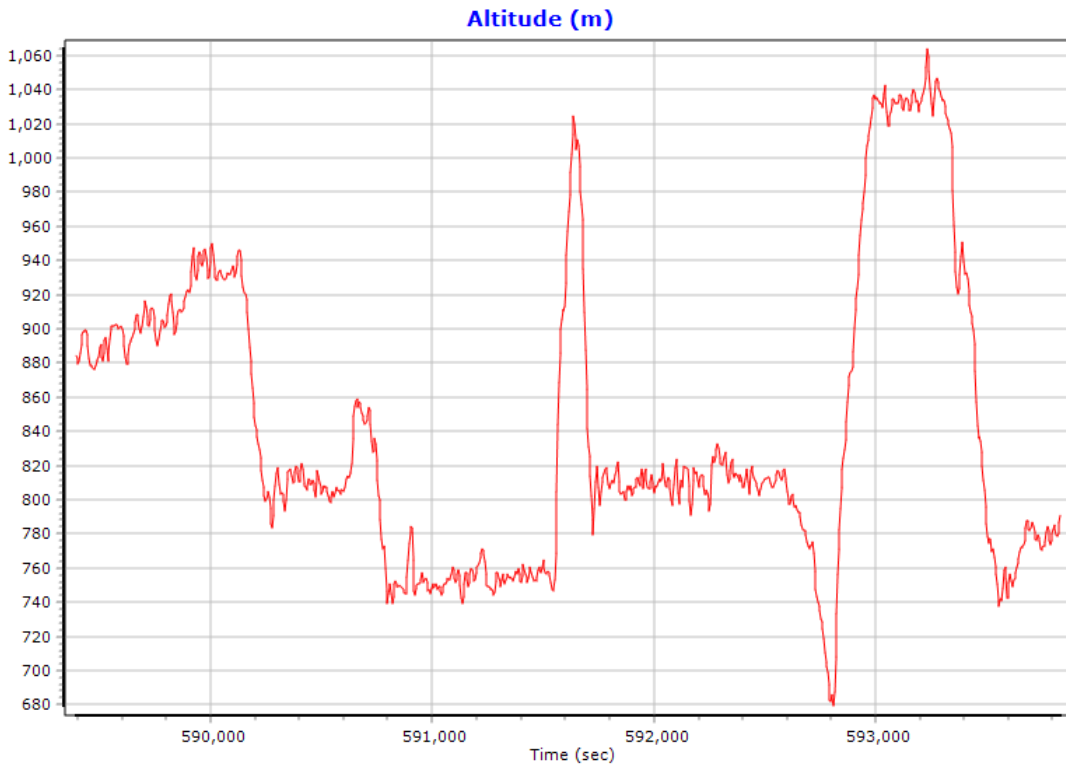
45A18244A

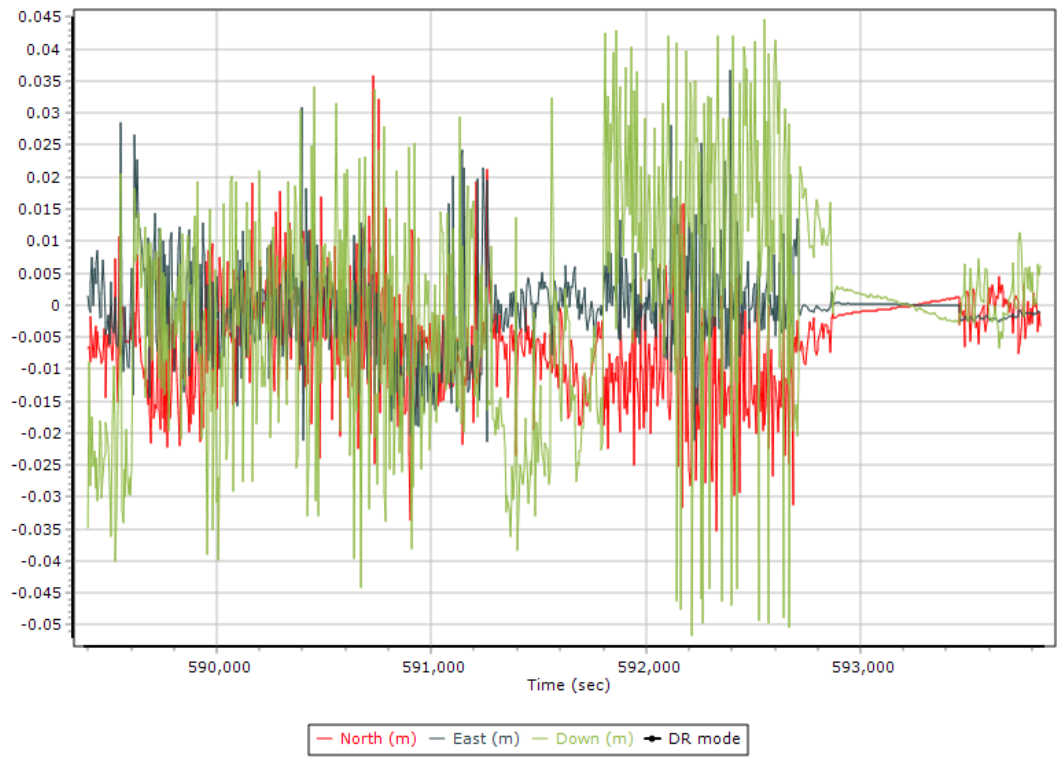
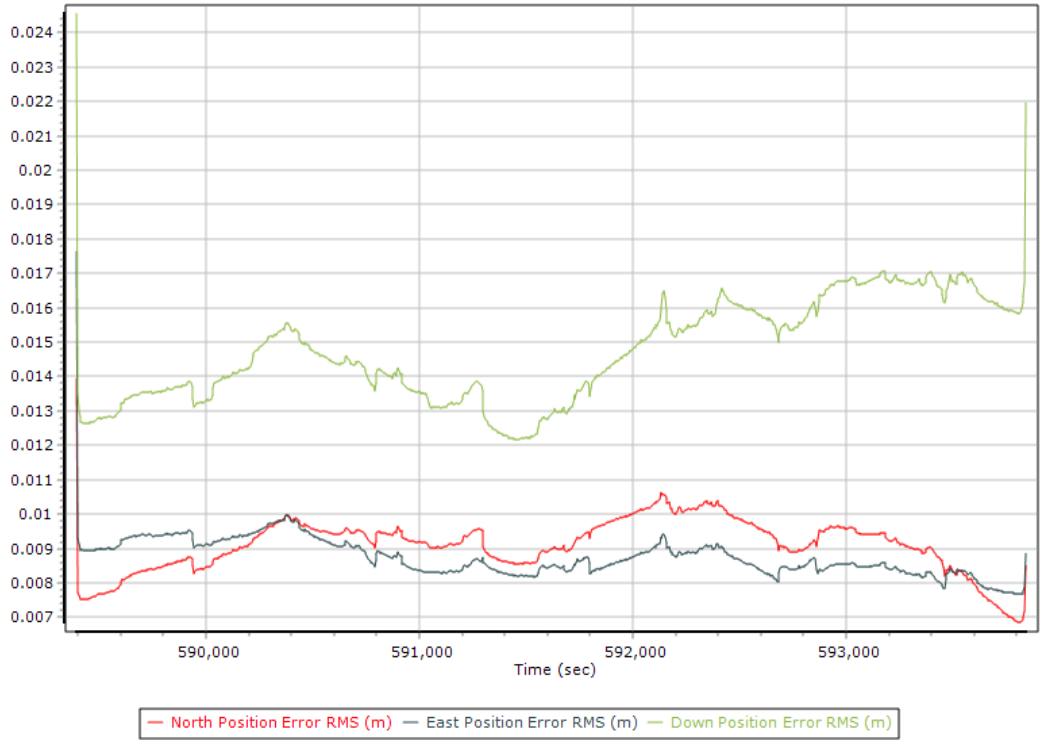


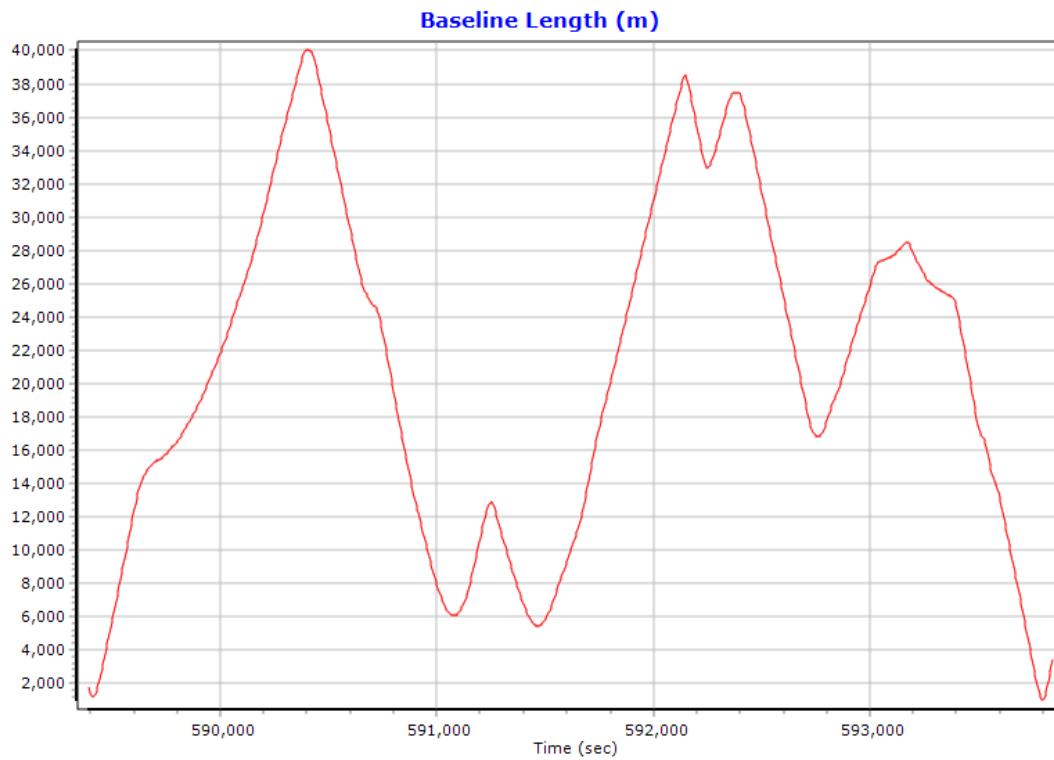
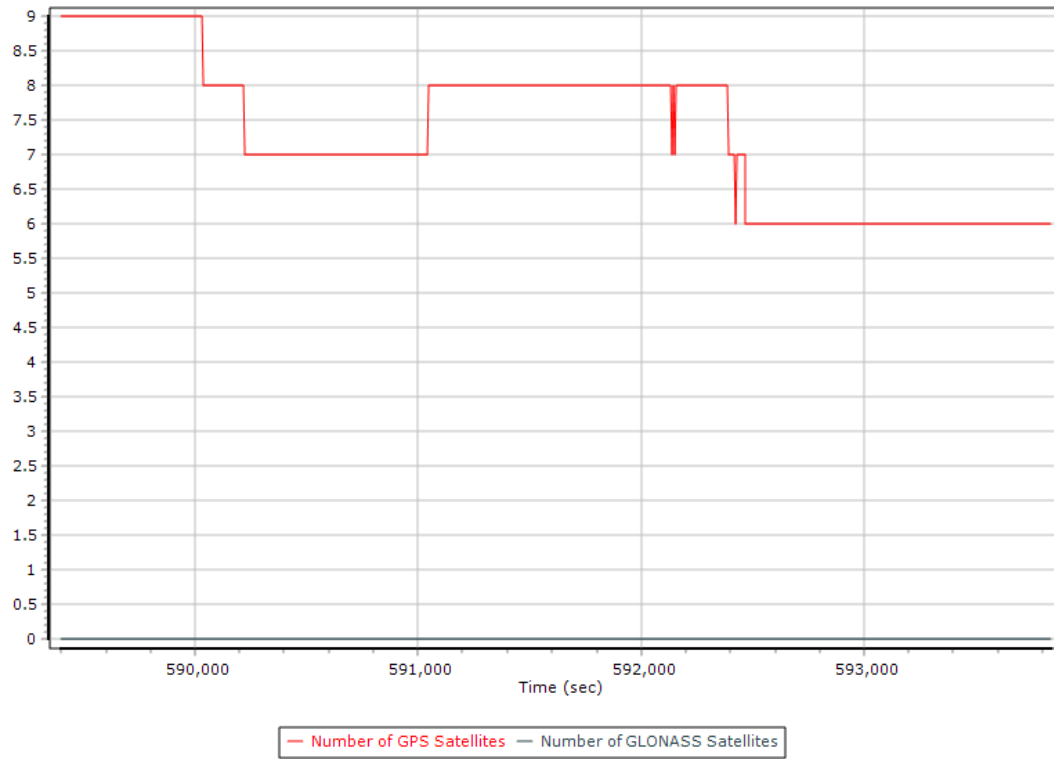
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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="3cm"/> <input type="radio"/> <3cm <input type="radio"/> 10cm <input type="radio"/> 50cm <input type="radio"/> 1m <input type="radio"/> 10m		

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

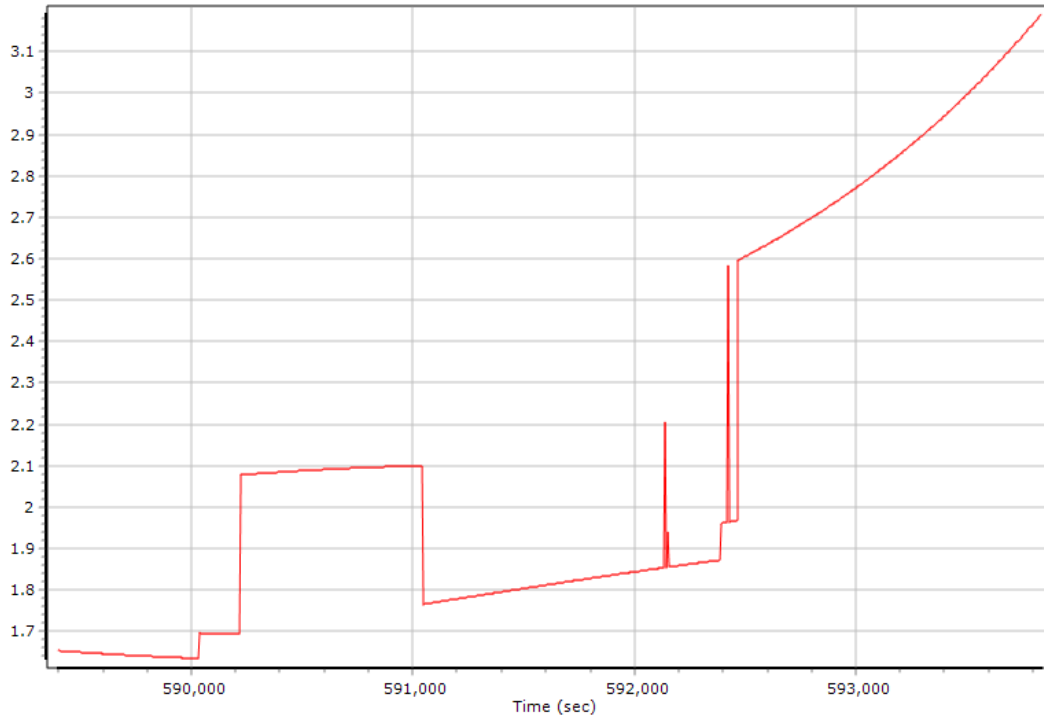
Timing	
Start	<input type="text" value="589393.135"/>
End	<input type="text" value="593844.007"/>
<input type="checkbox"/> Entire time interval	
<input checked="" type="checkbox"/> Seconds of start week	
UTC Offset	<input type="text" value="18.000"/>
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



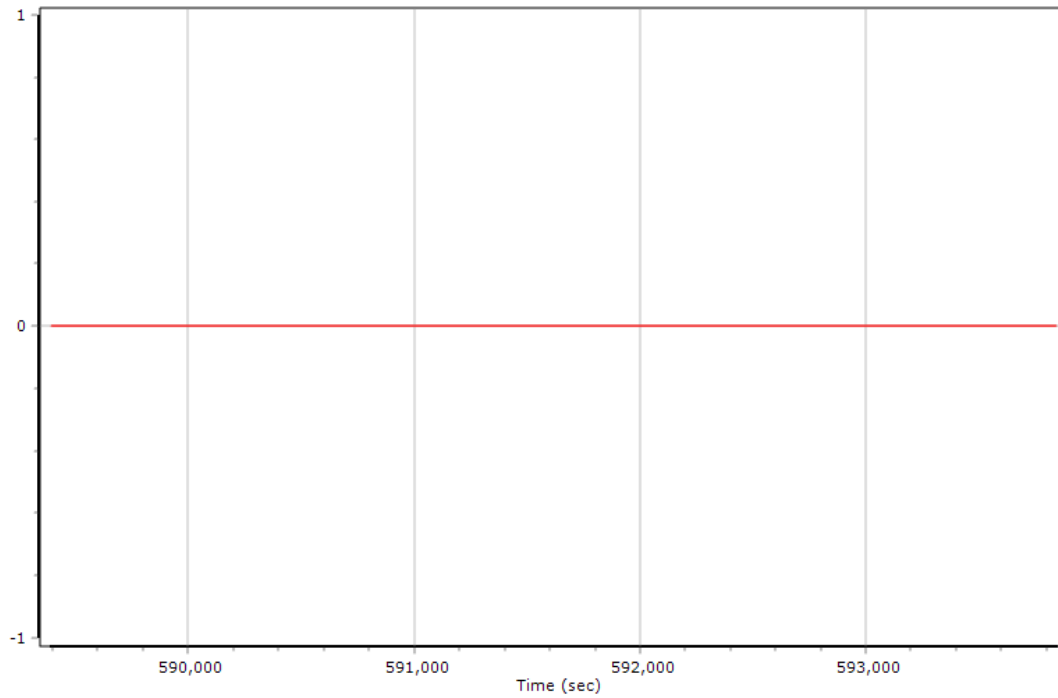




PDOP

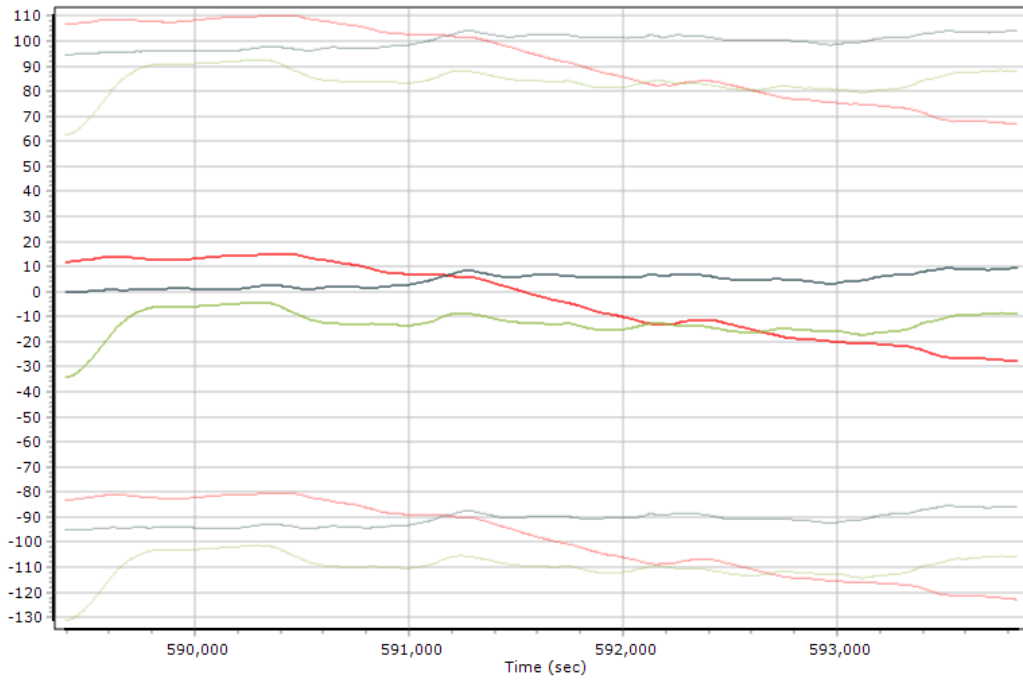


Processing mode

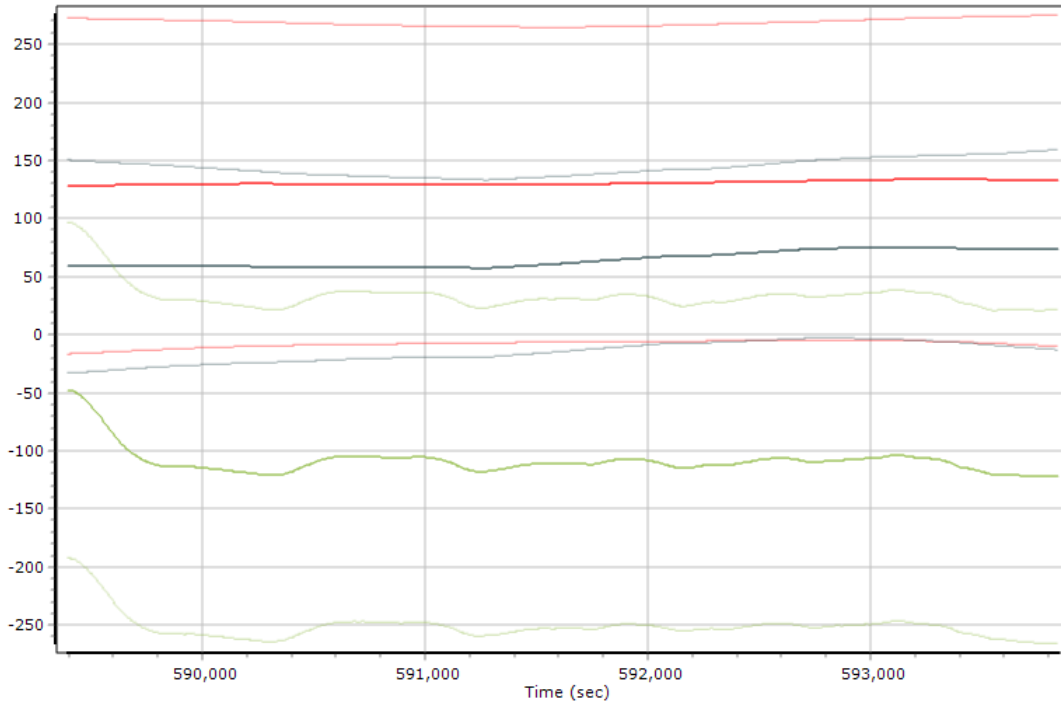


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

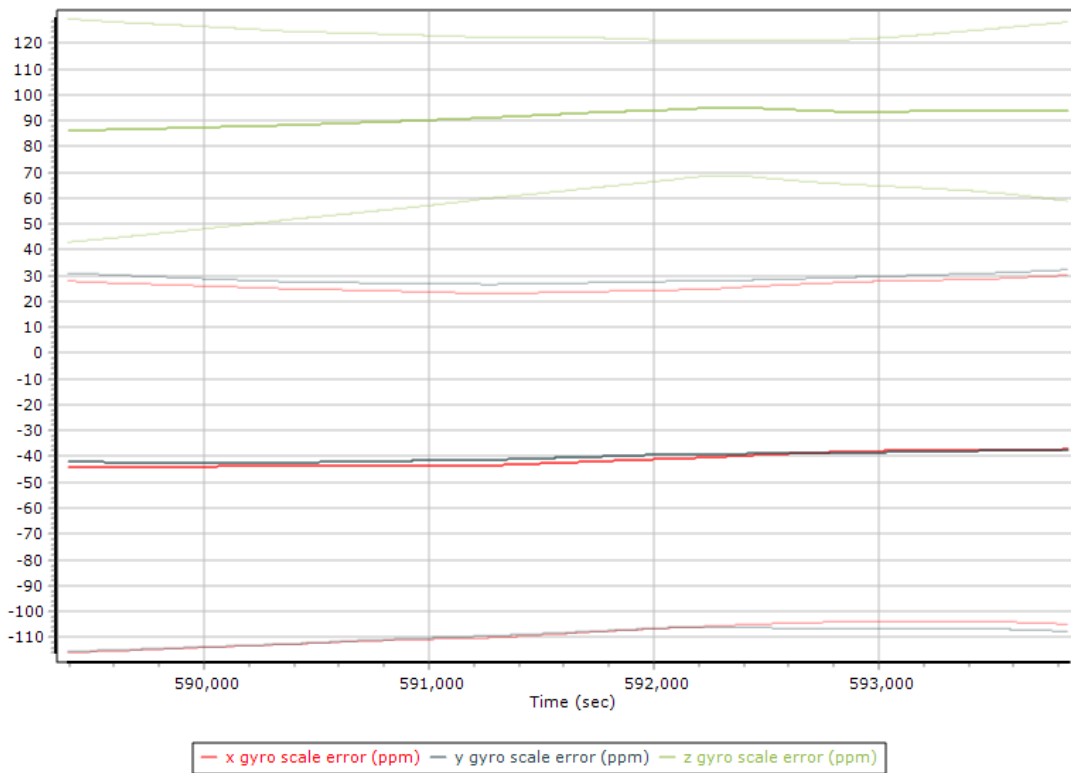
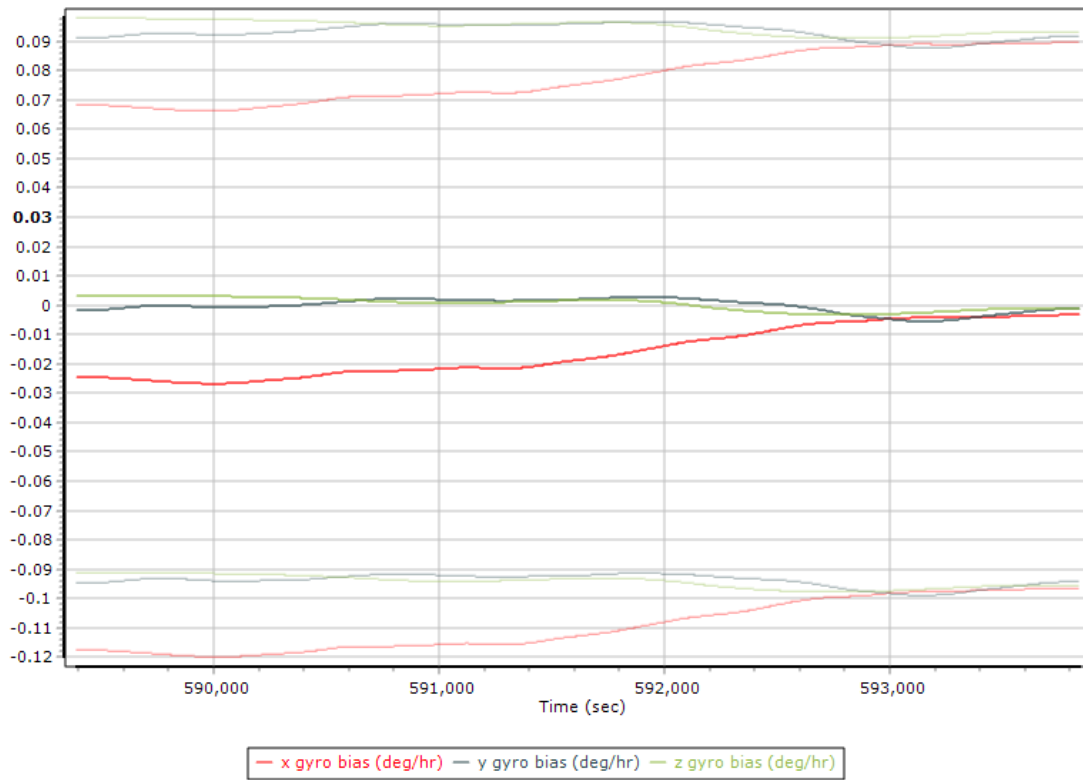
Sensor Errors



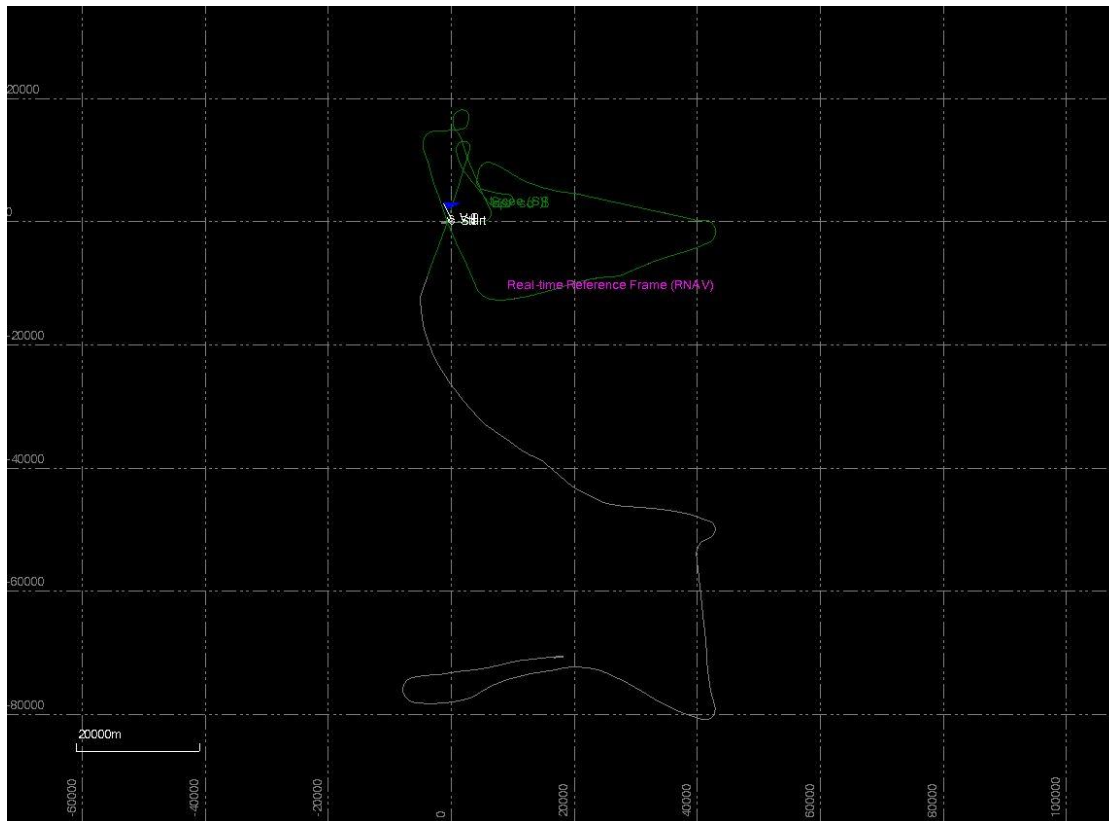
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



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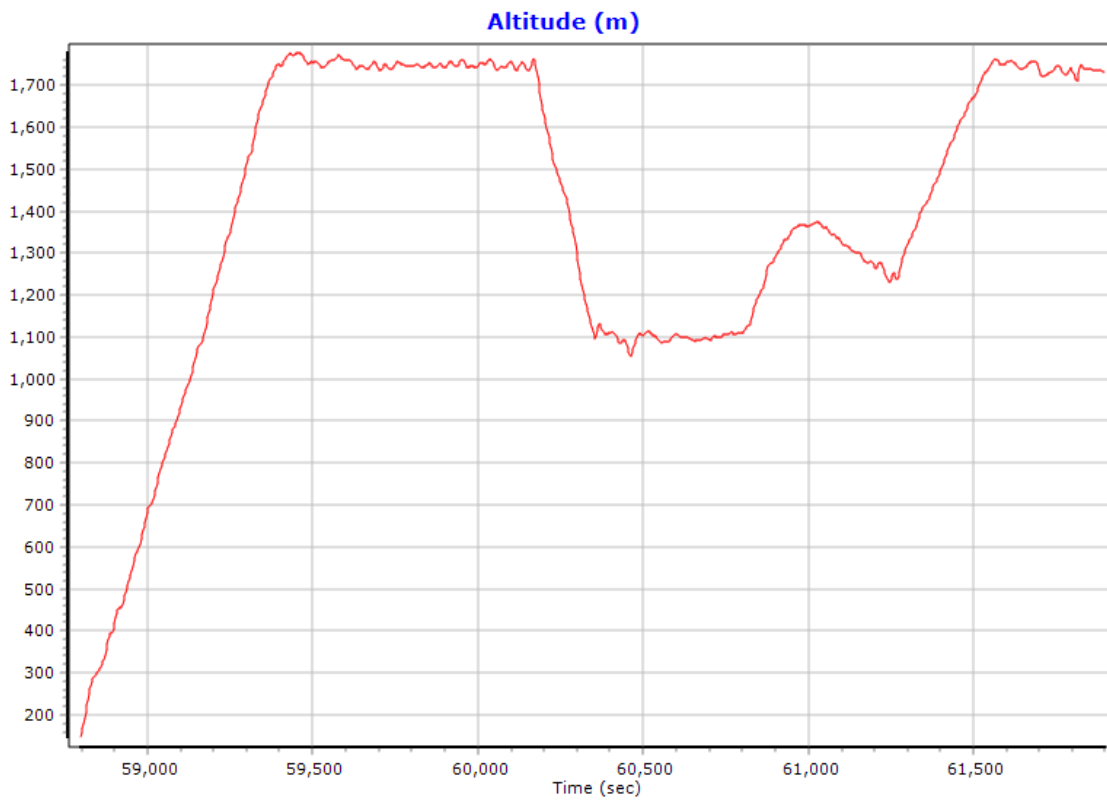
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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			

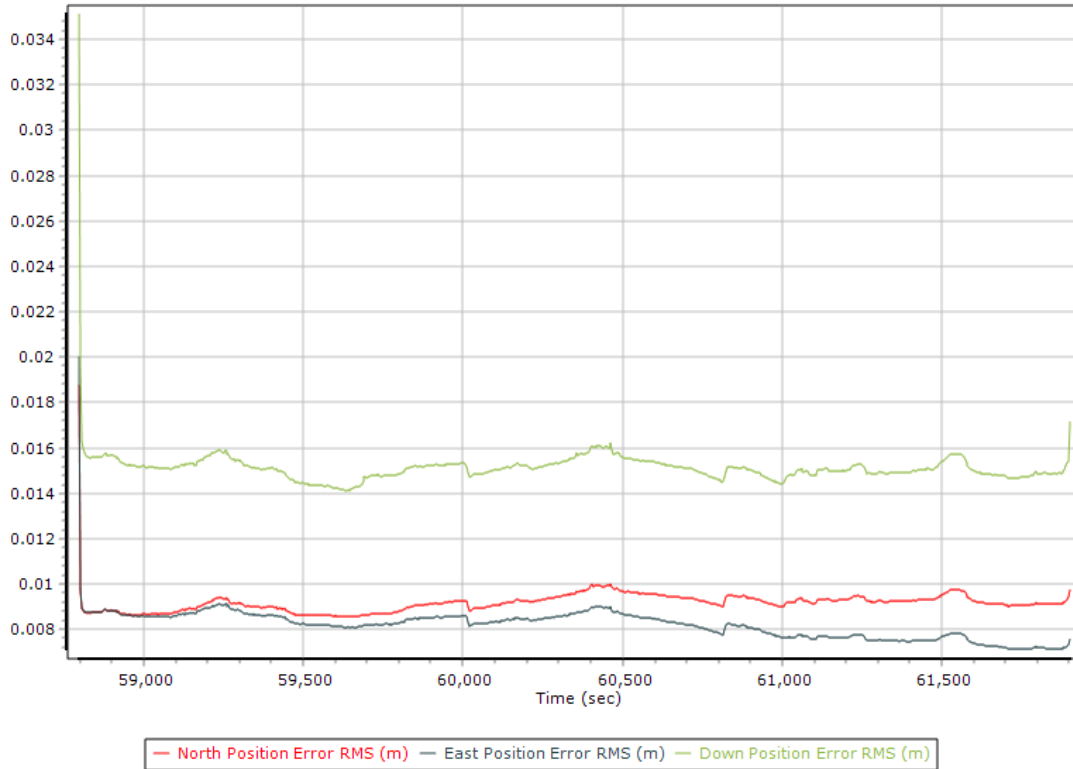
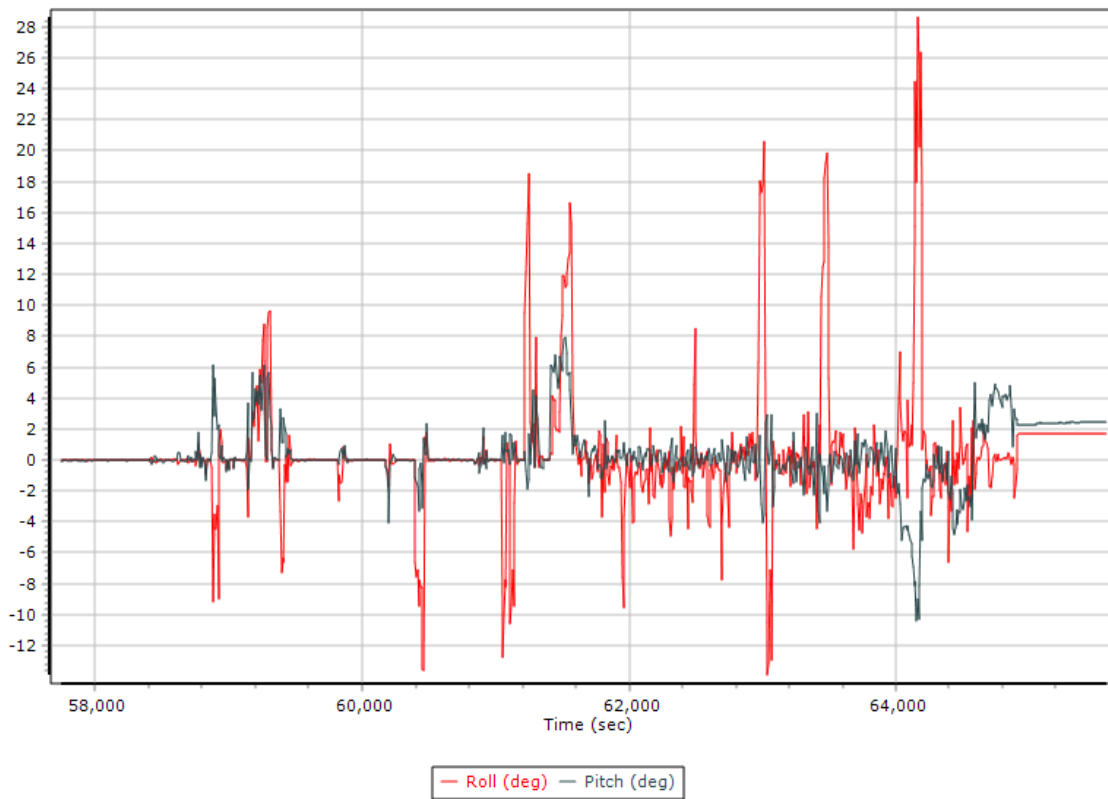
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

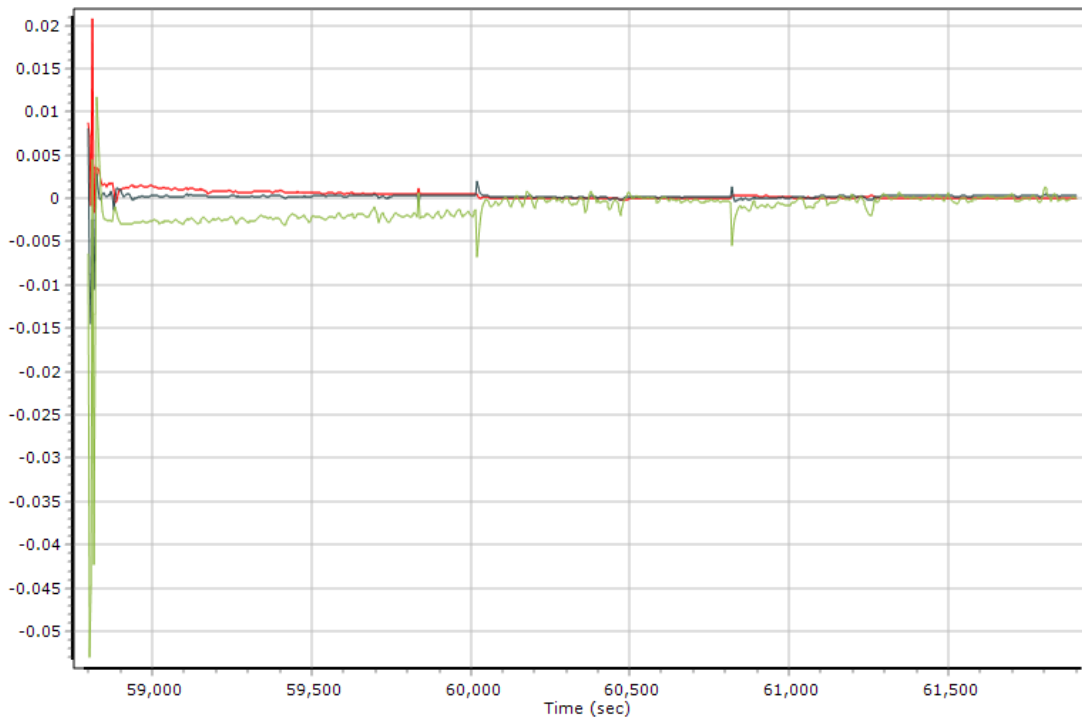
Timing

Start	58797.416	Data	Incr. (sec)
End	61905.020	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

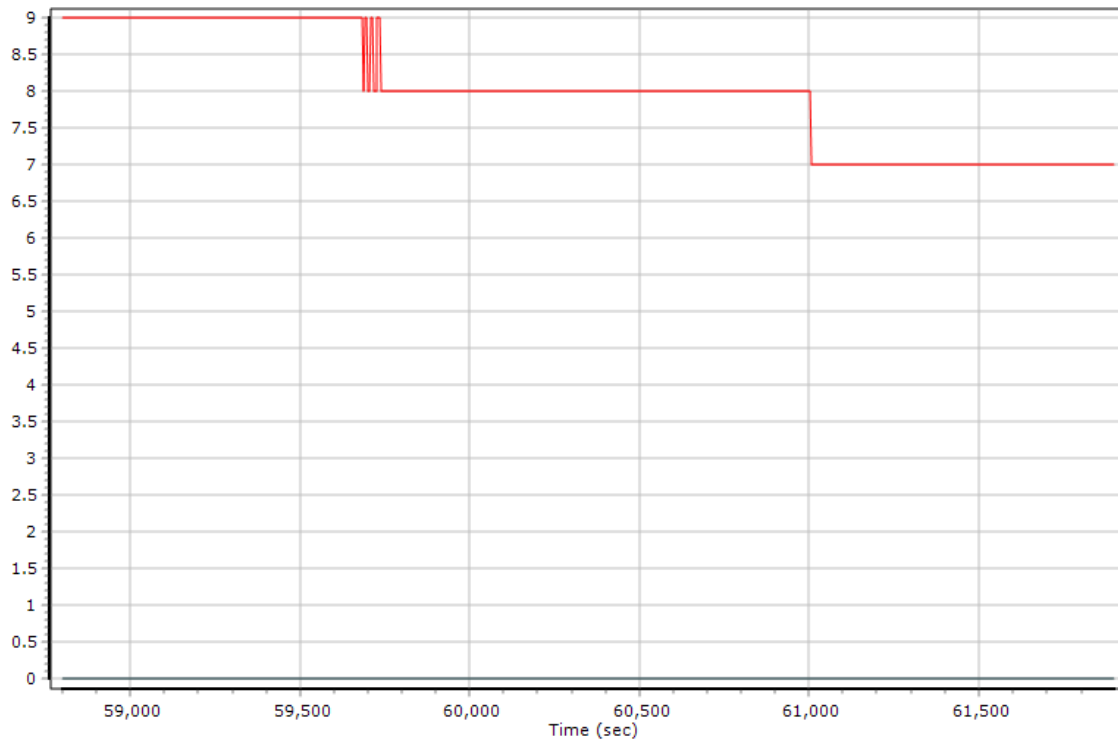
UTC Offset: 18.000



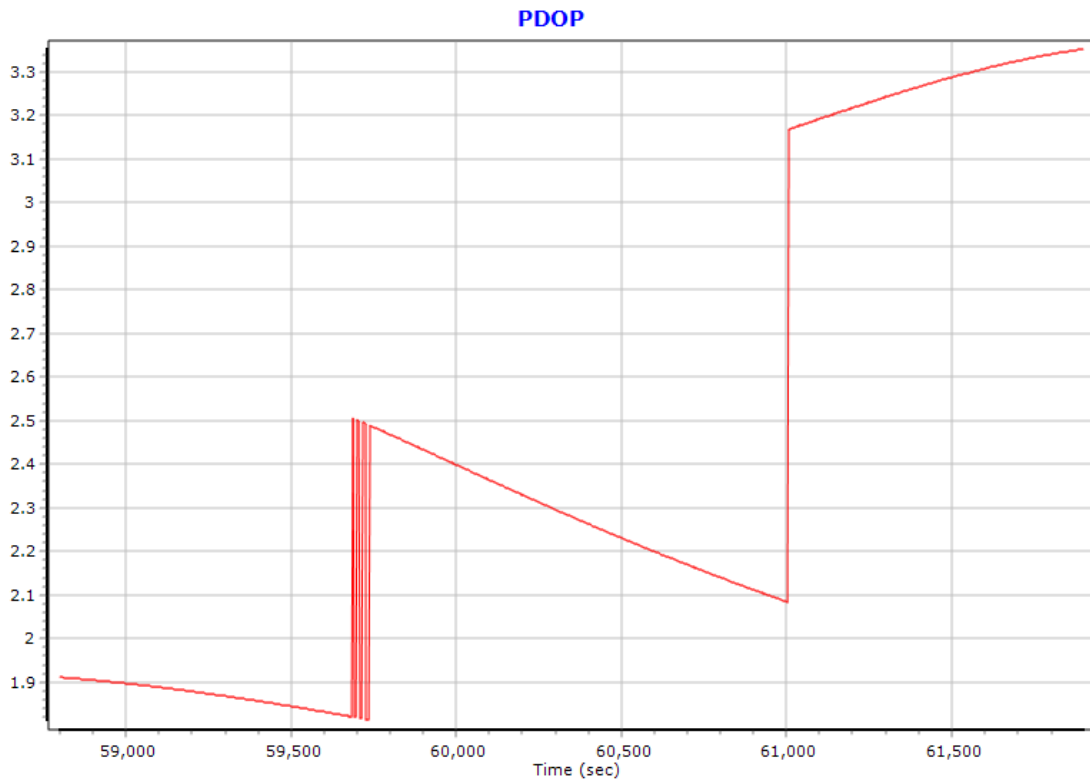
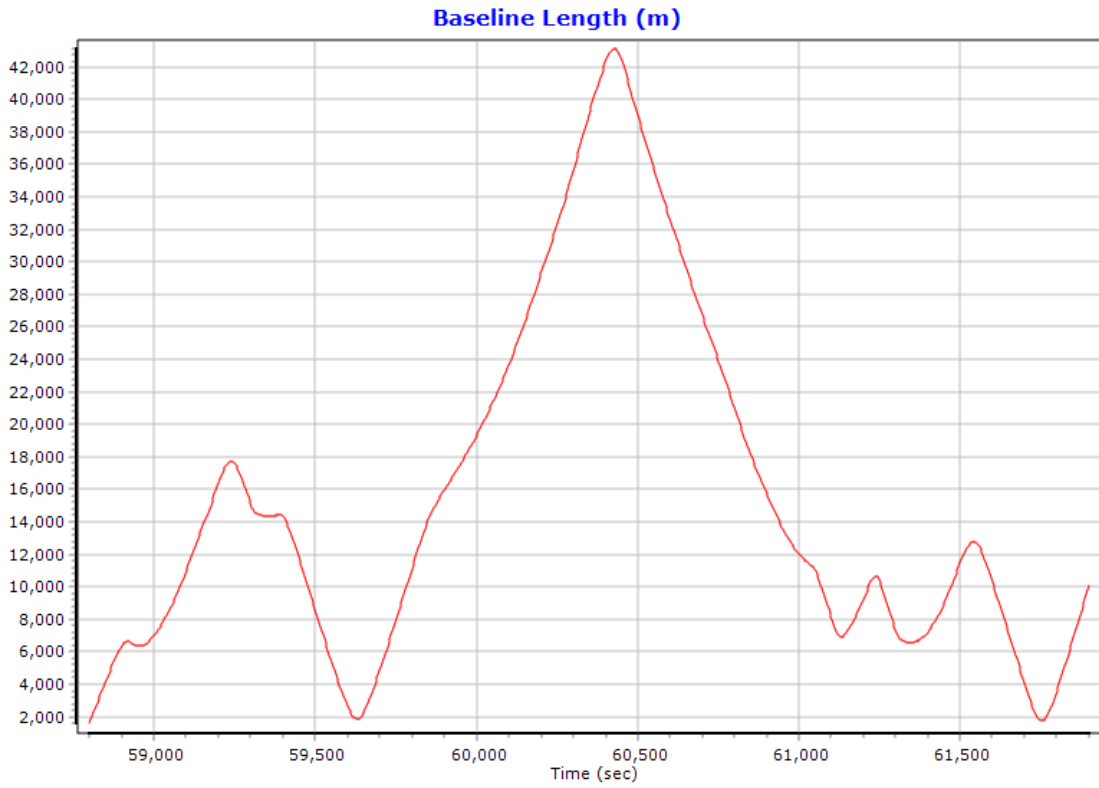




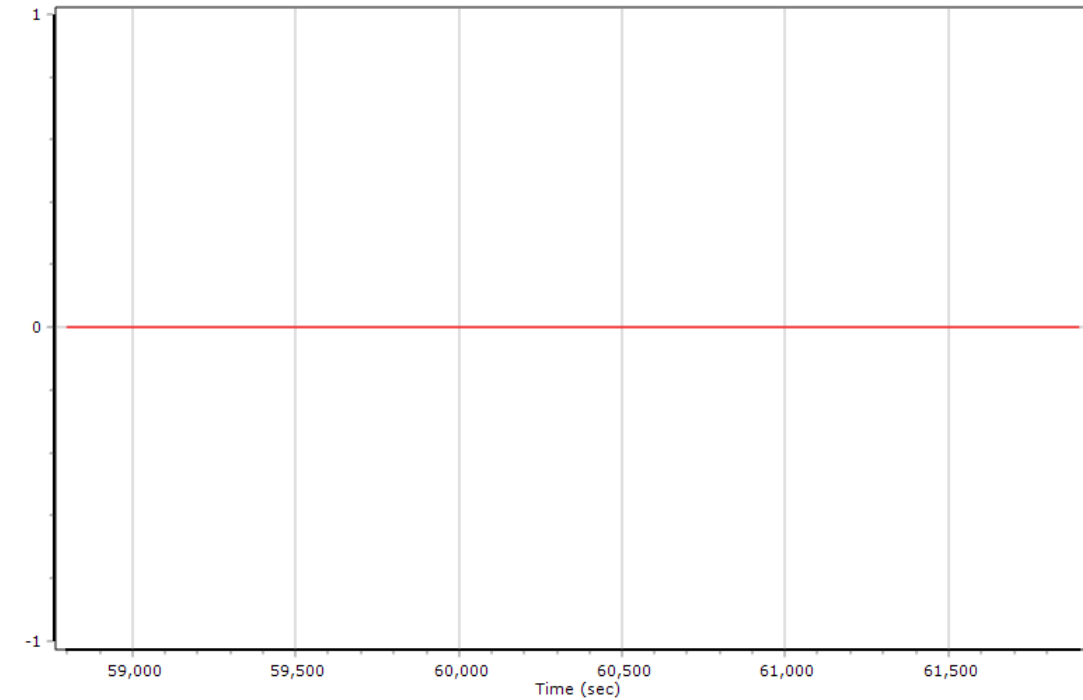
— North (m) — East (m) — Down (m) — DR mode



— Number of GPS Satellites — Number of GLONASS Satellites

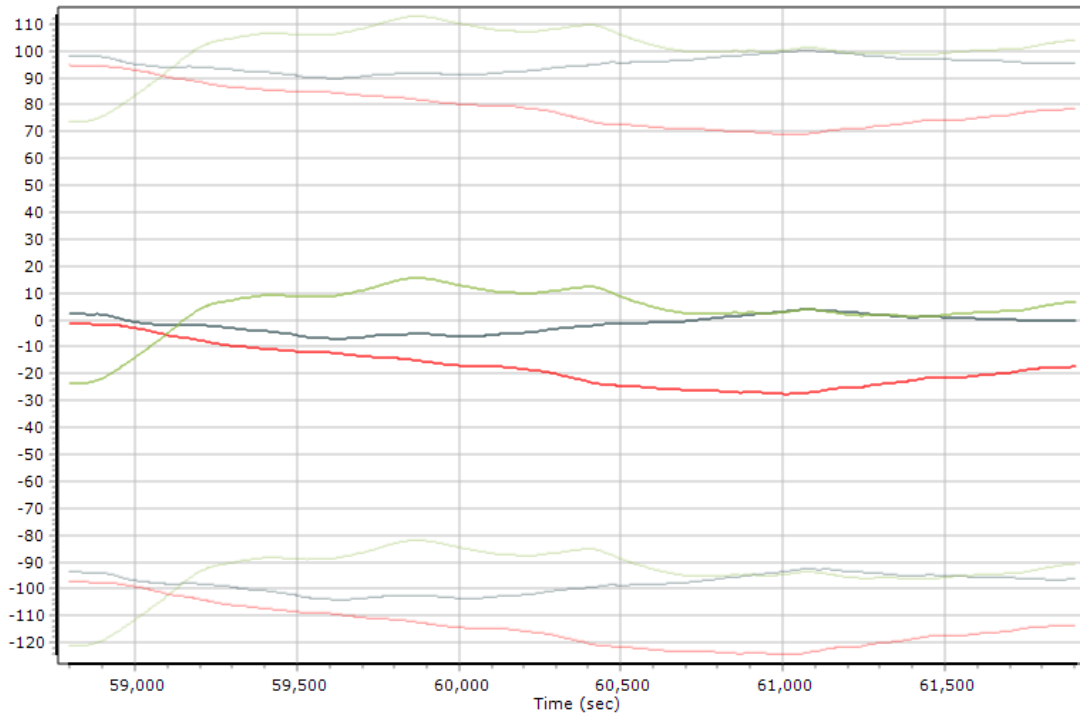


Processing mode

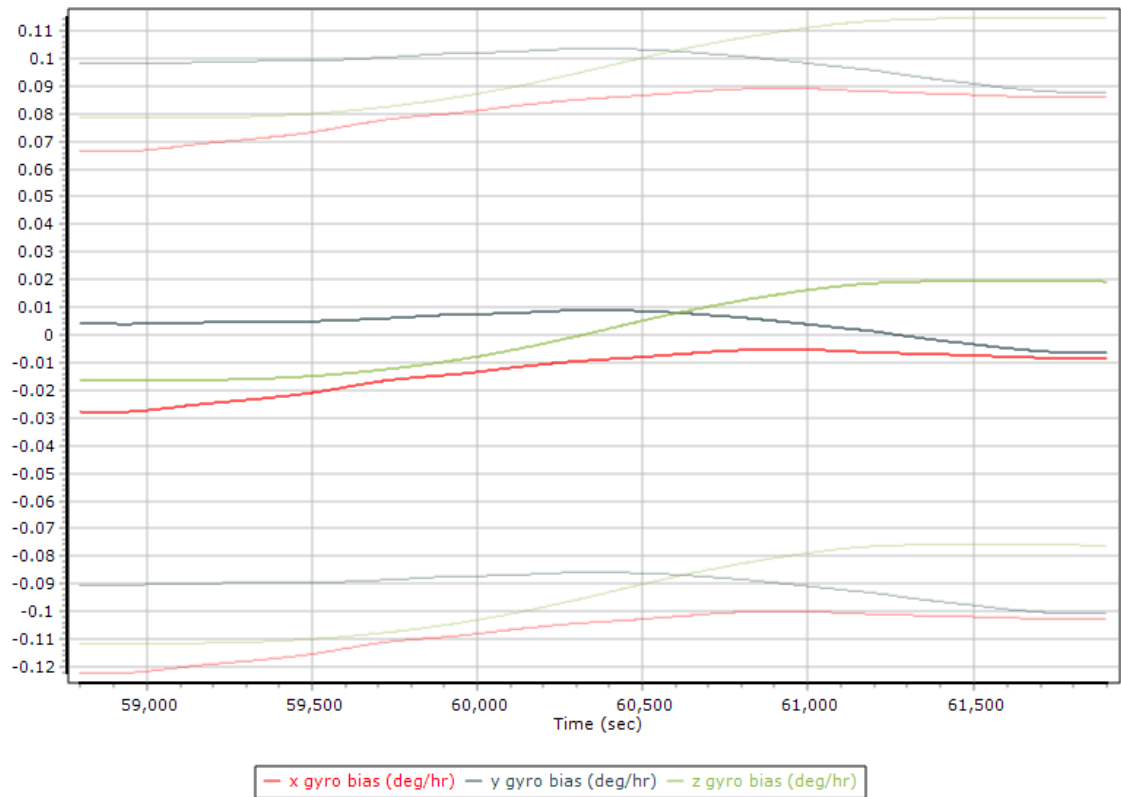
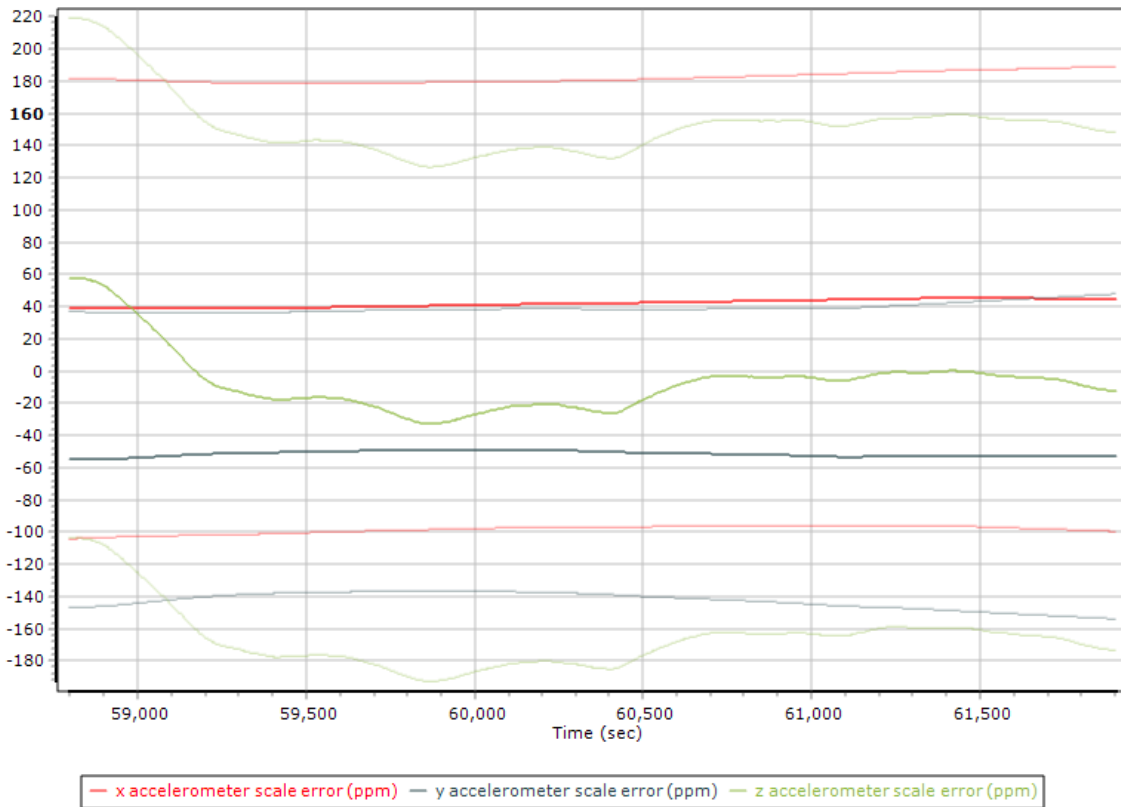


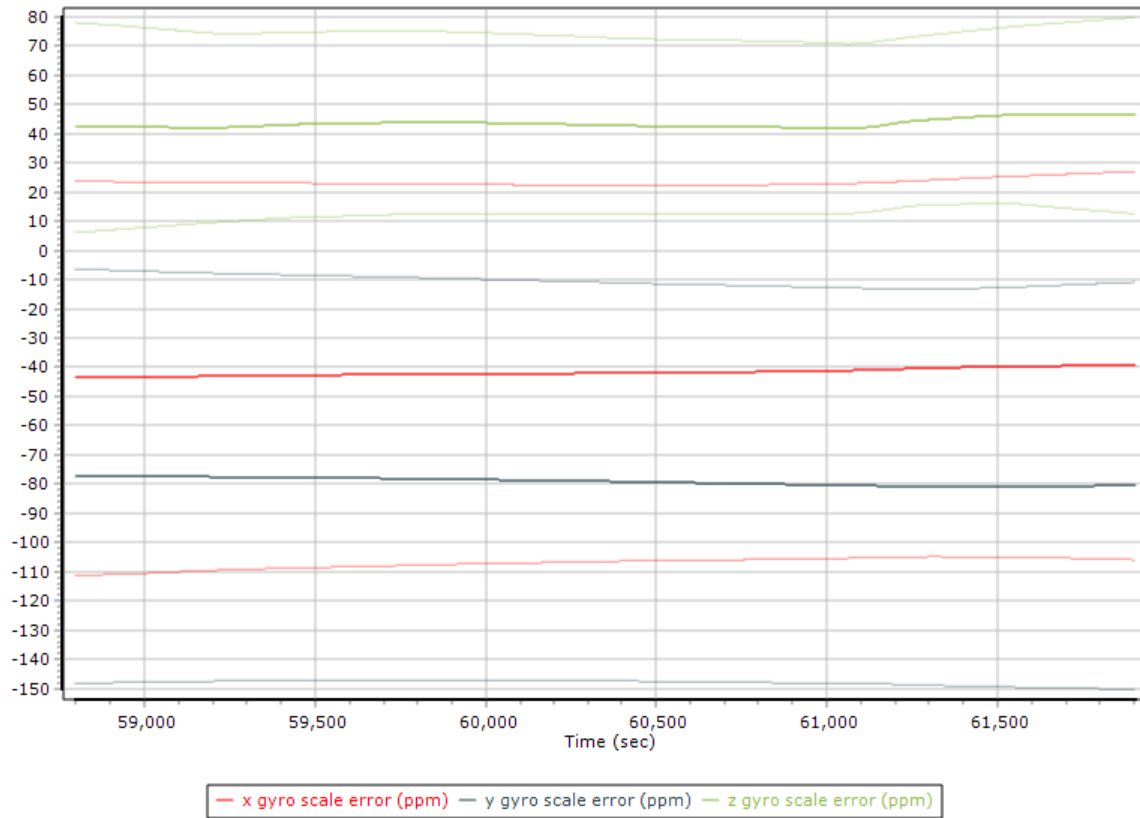
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

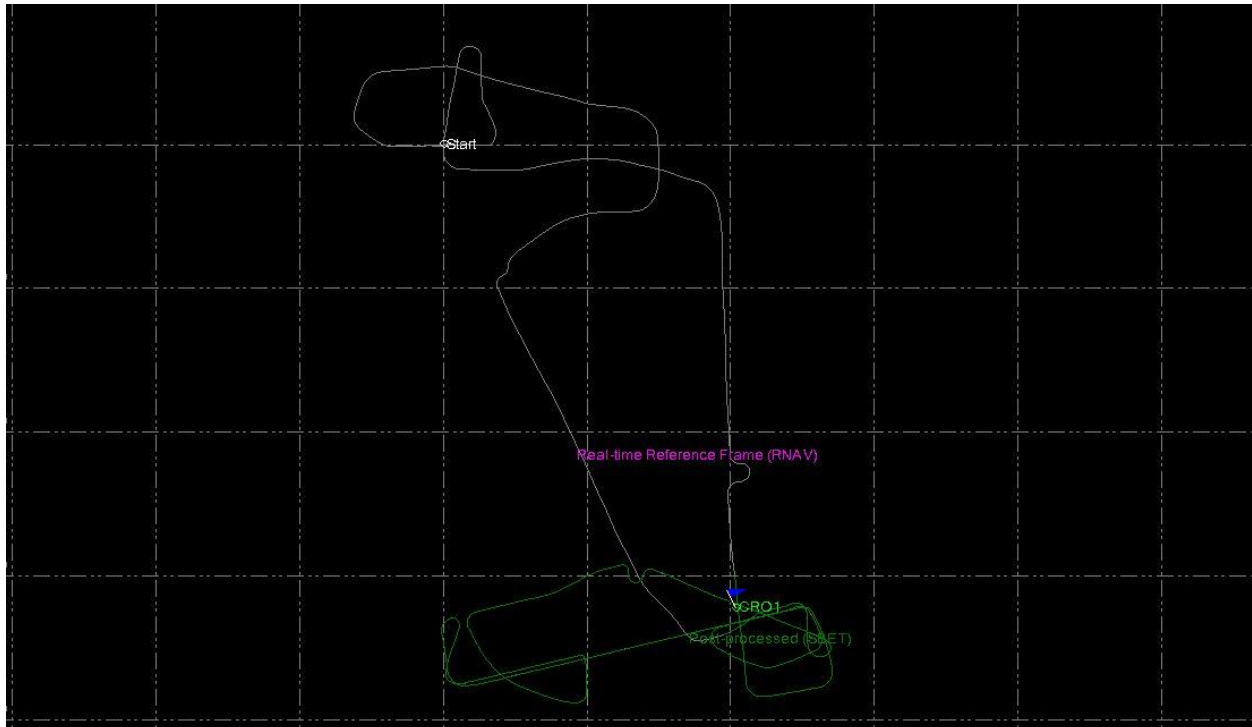


— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)





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Stabilized Mount to IMU Lever Arm

X:

Y:

Z:

Stabilized Mount to IMU Mounting Angles

X:

Y:

Z:

Stabilized Mount to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

Aircraft to Stabilized Mount Mounting Angles

X:

Y:

Z:

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

Timing

Start:

End:

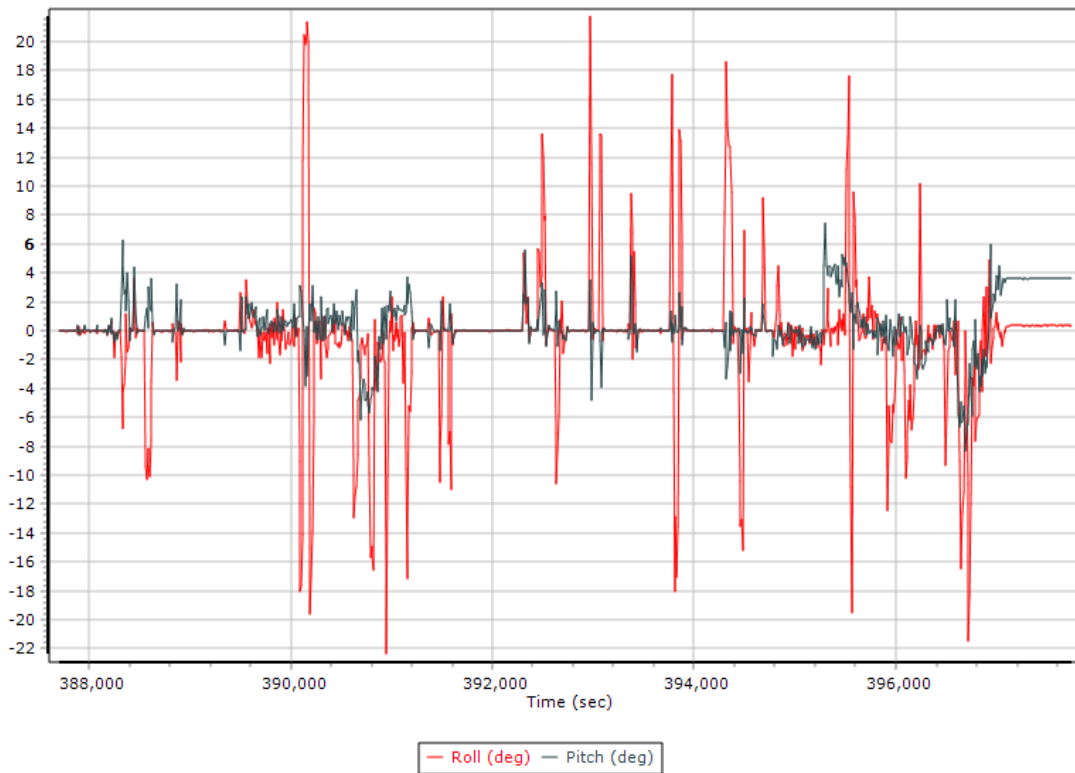
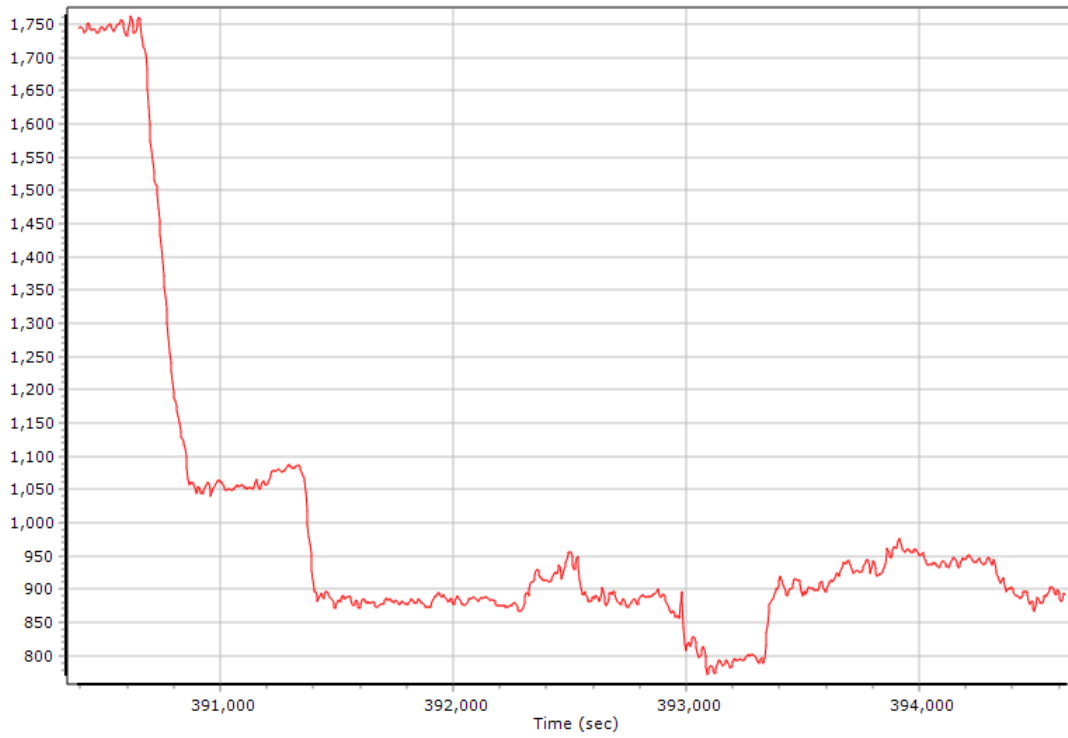
Entire time interval

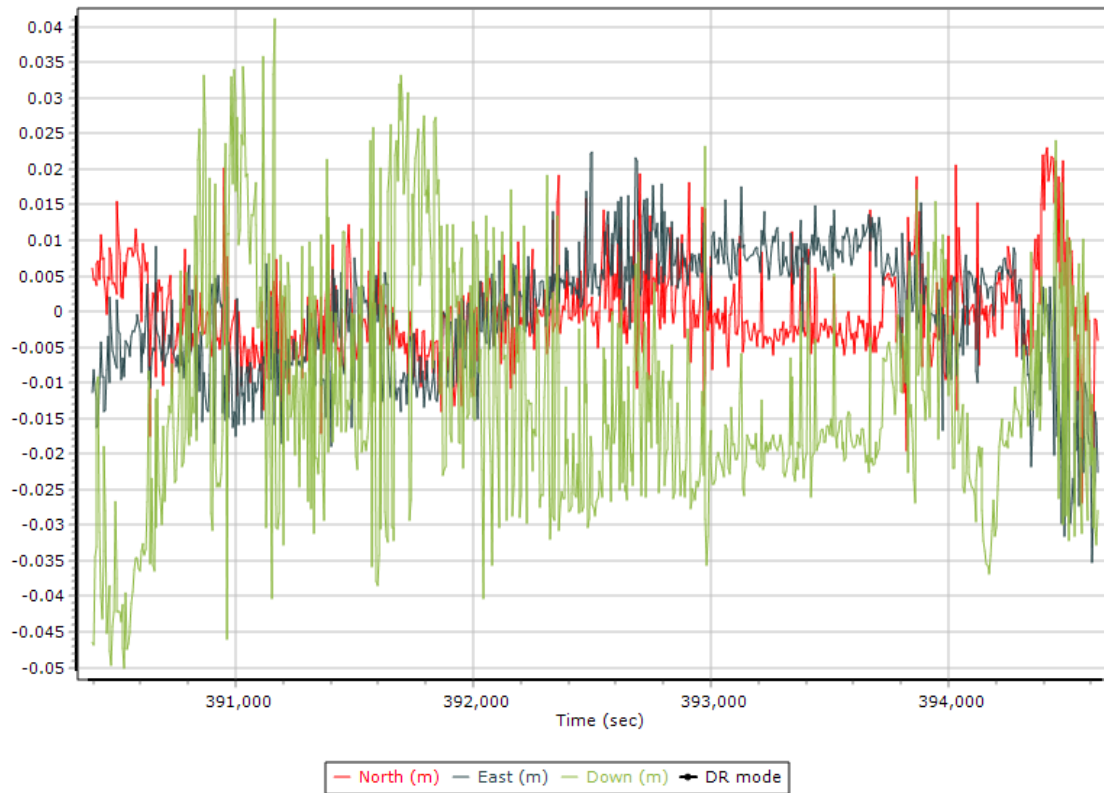
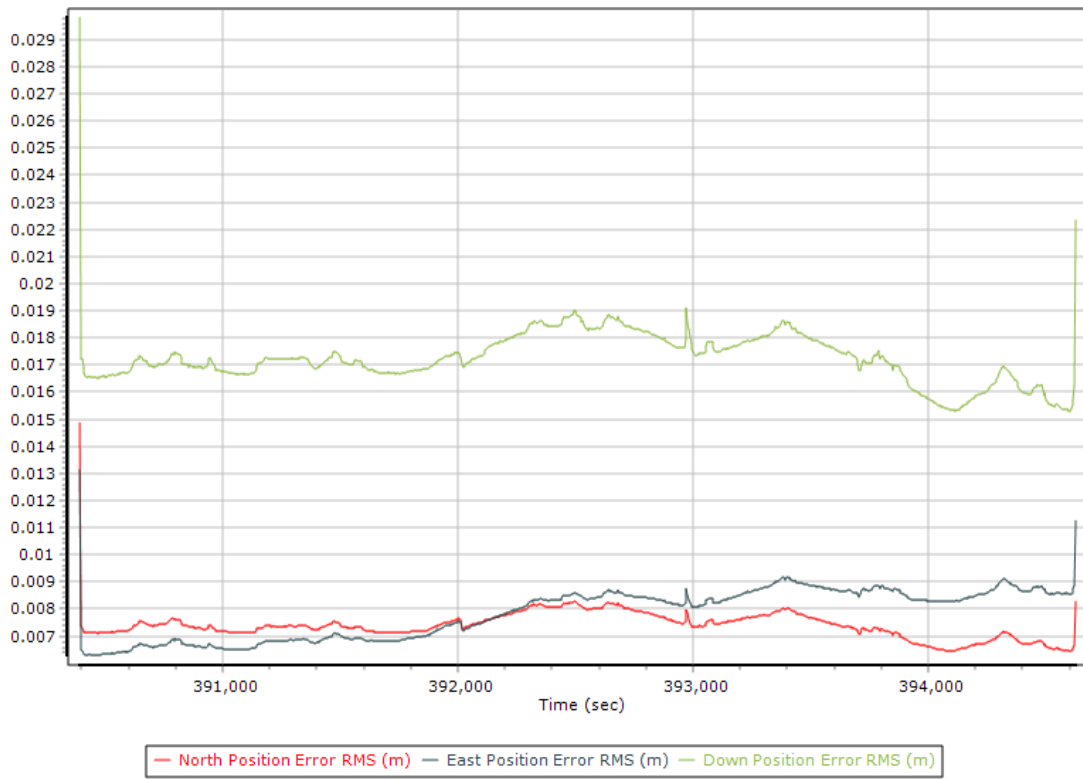
Seconds of start week

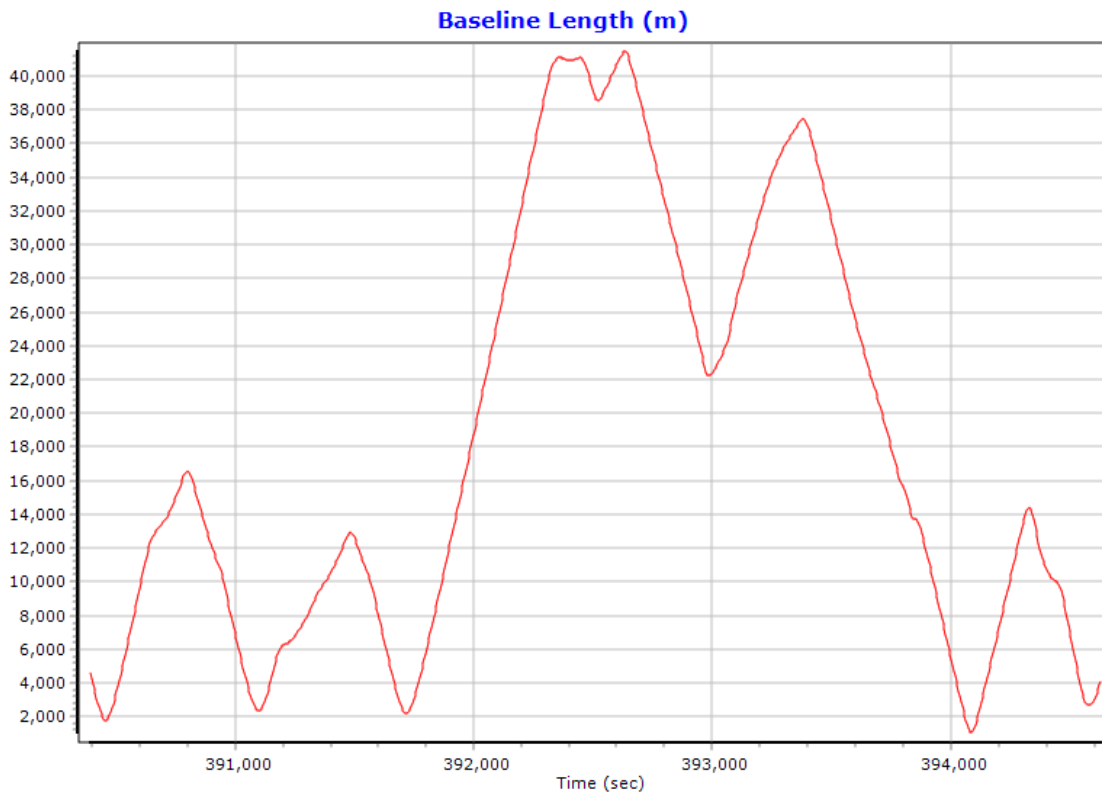
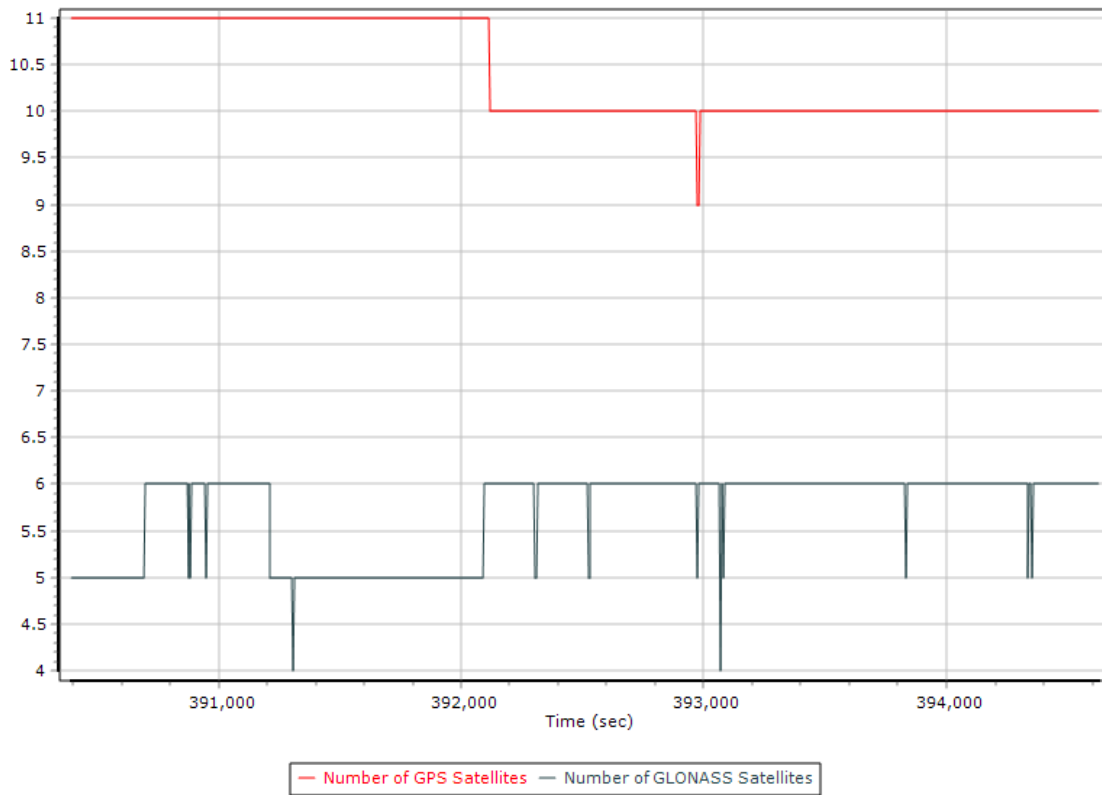
UTC Offset:

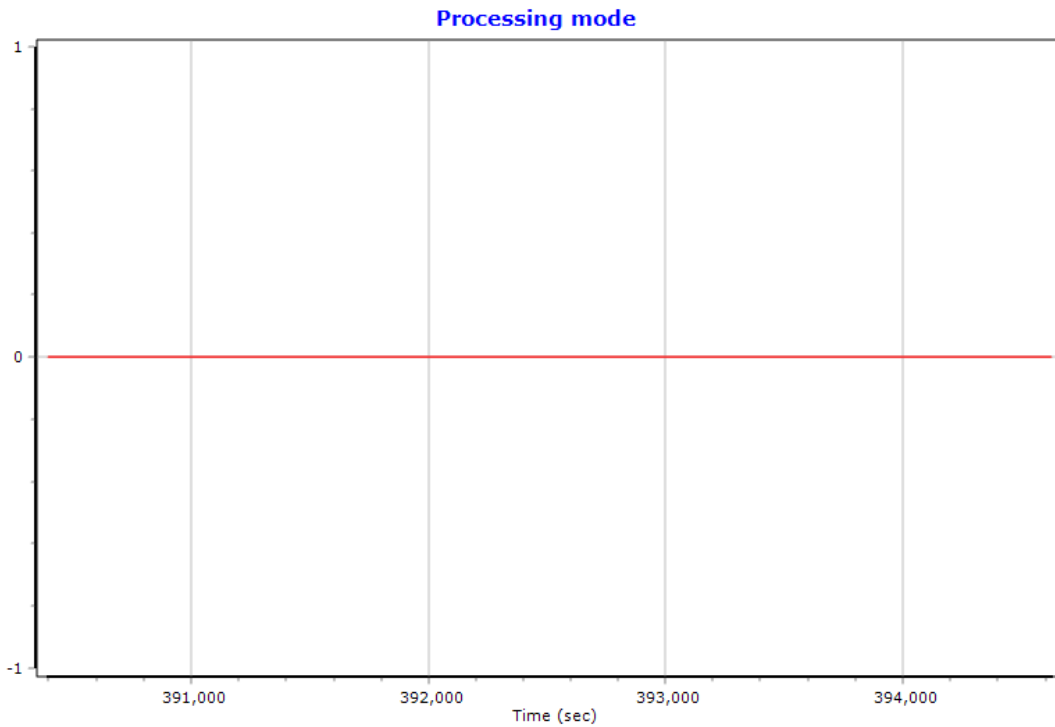
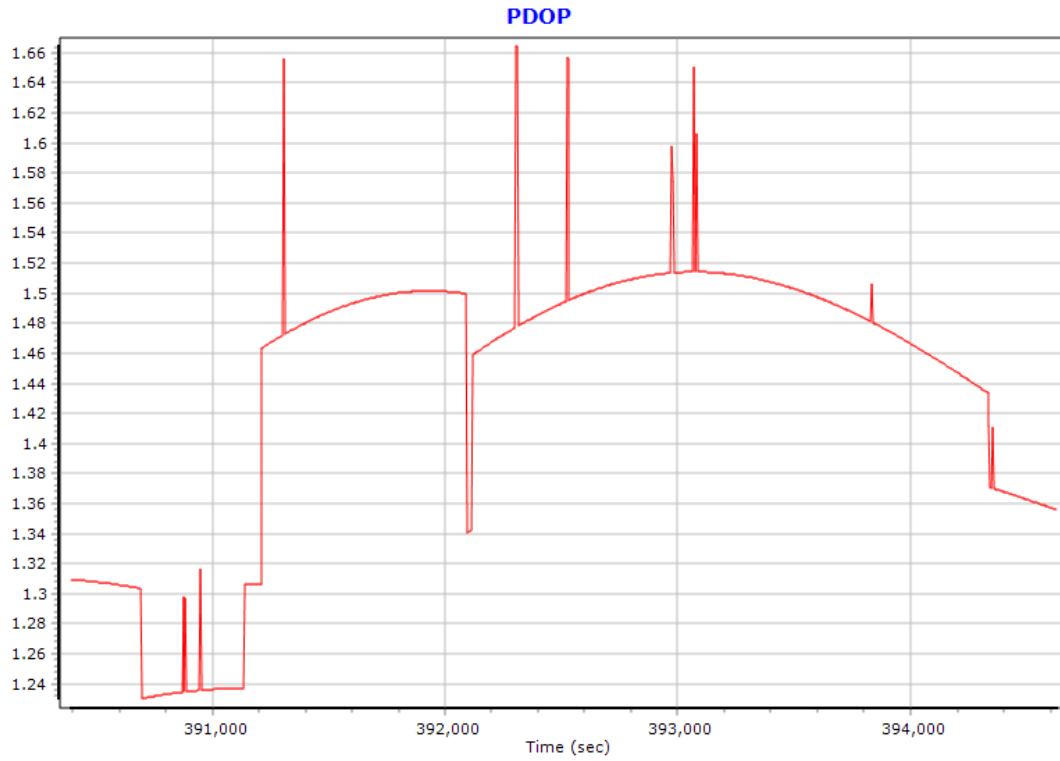
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

Altitude (m)



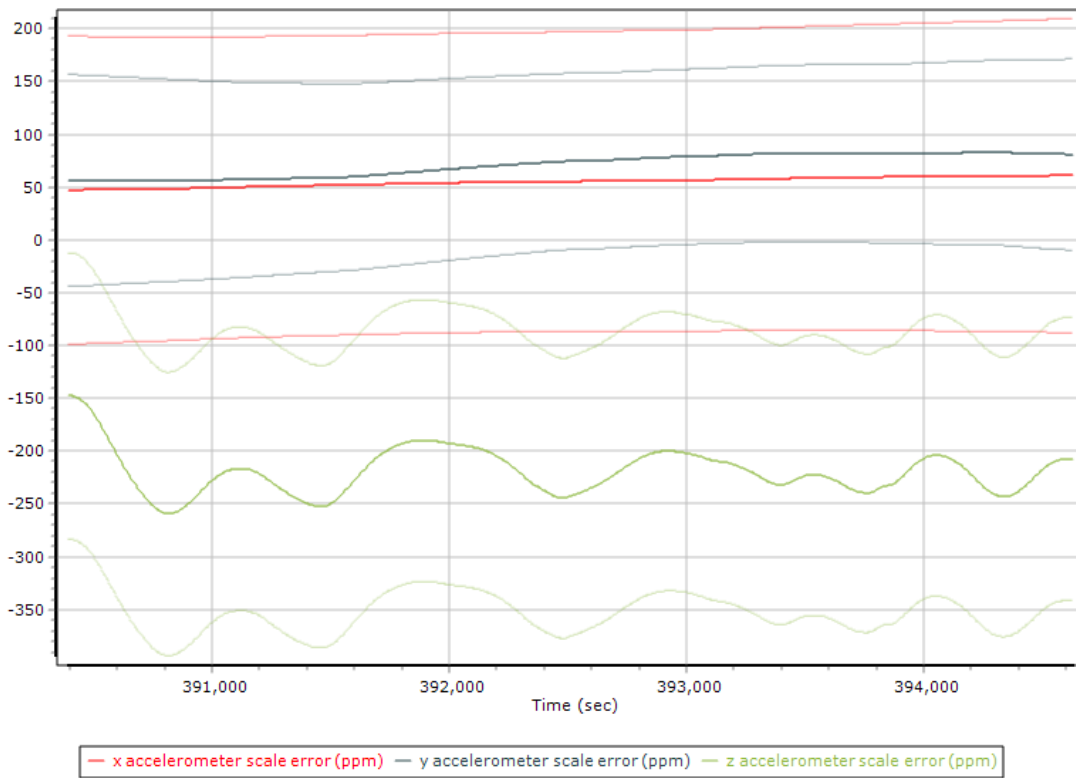
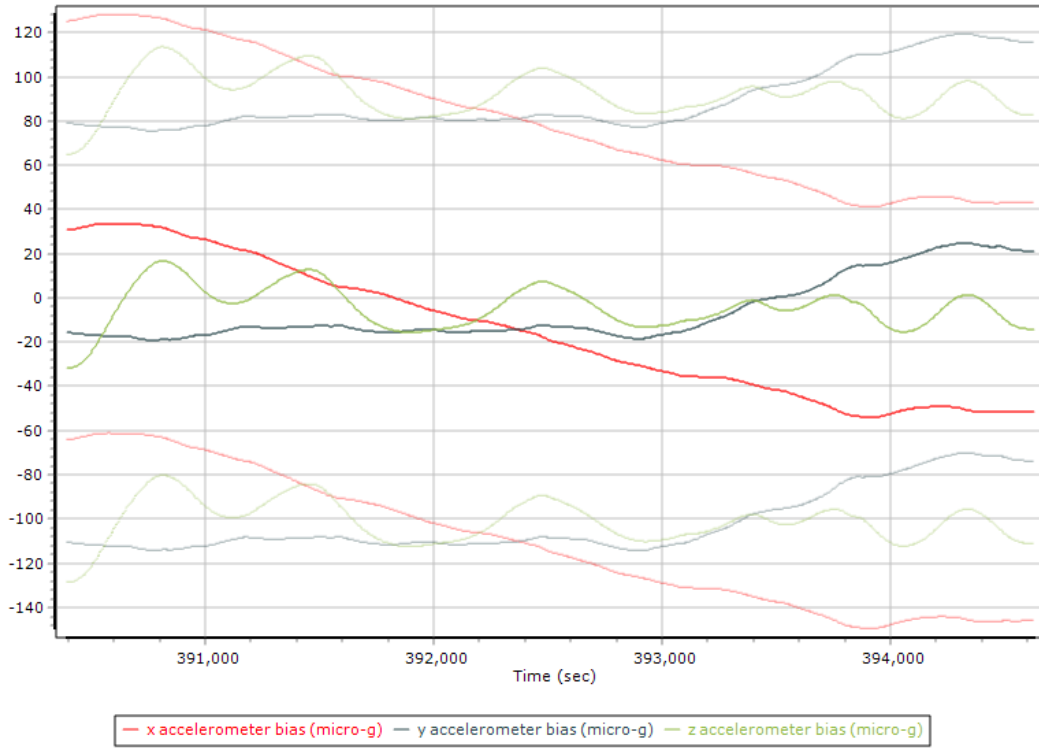


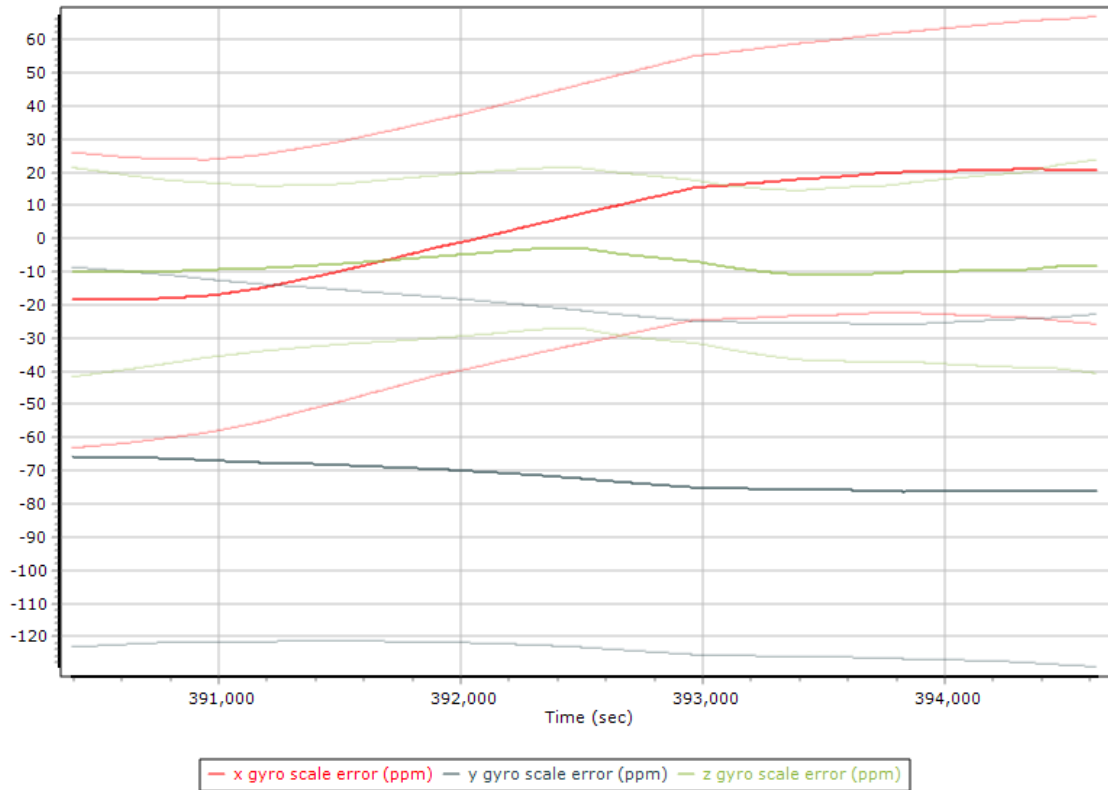
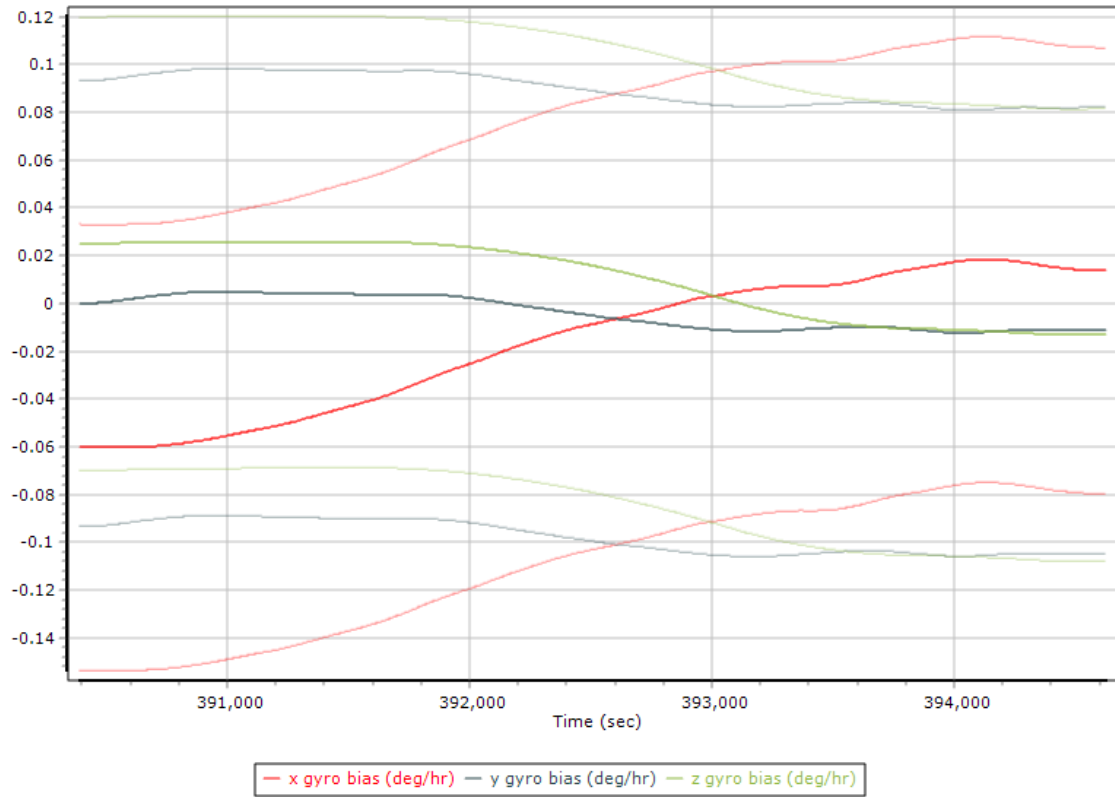




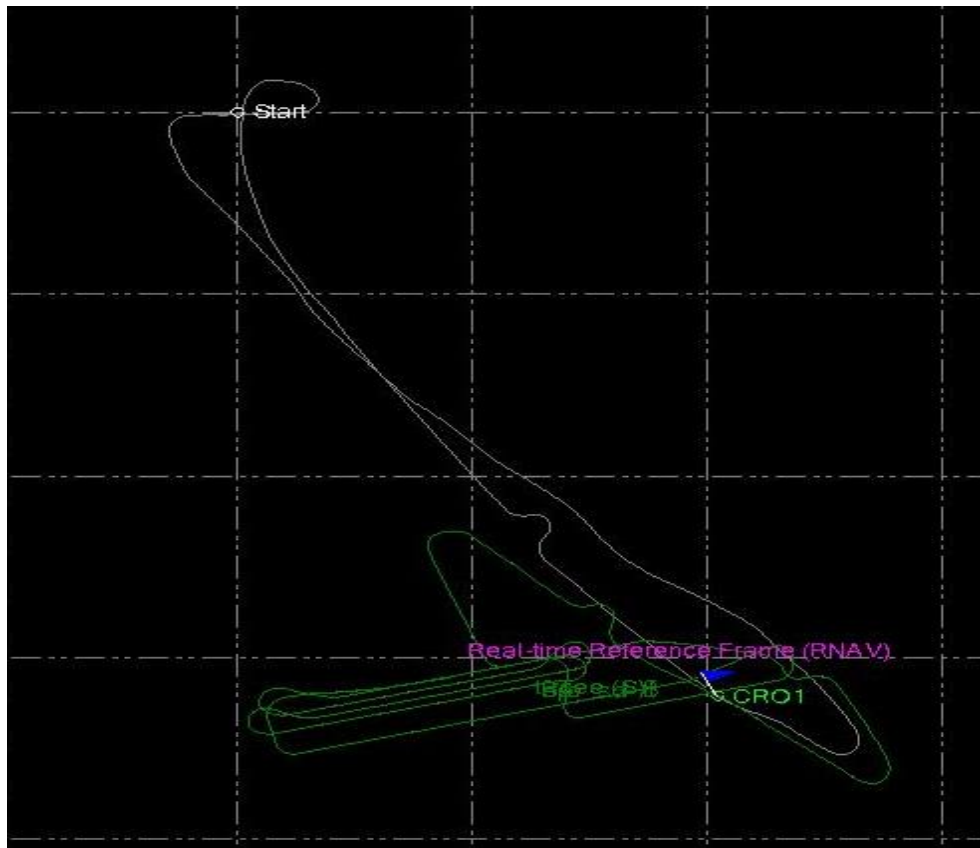
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





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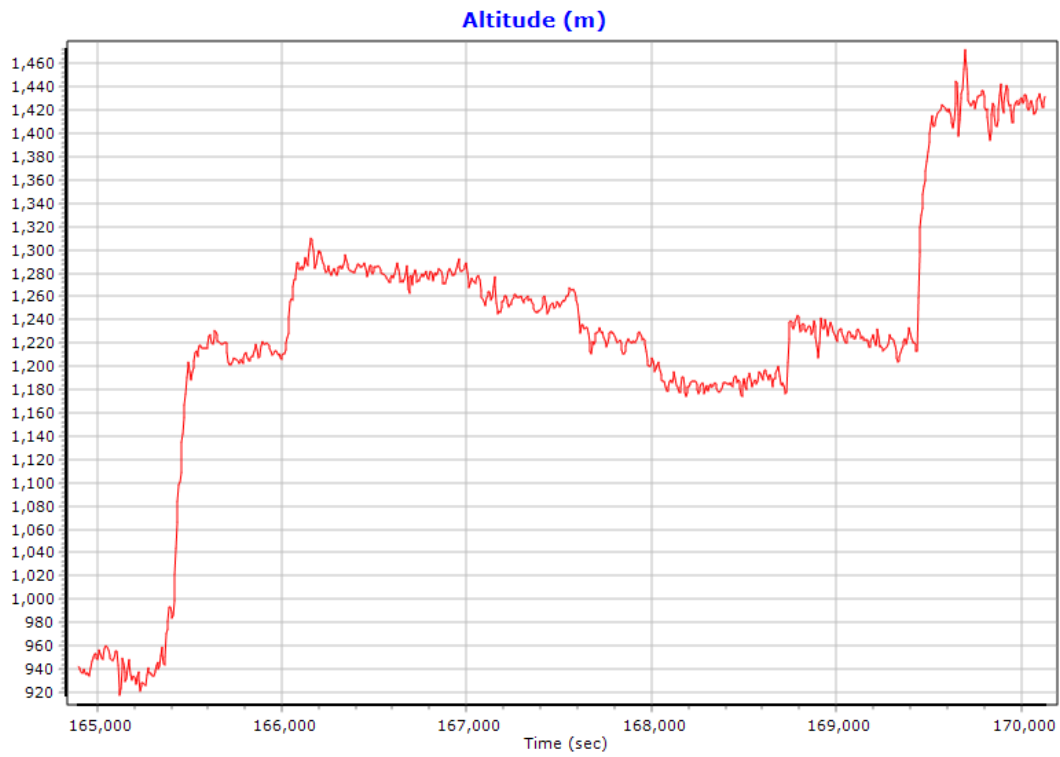
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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		

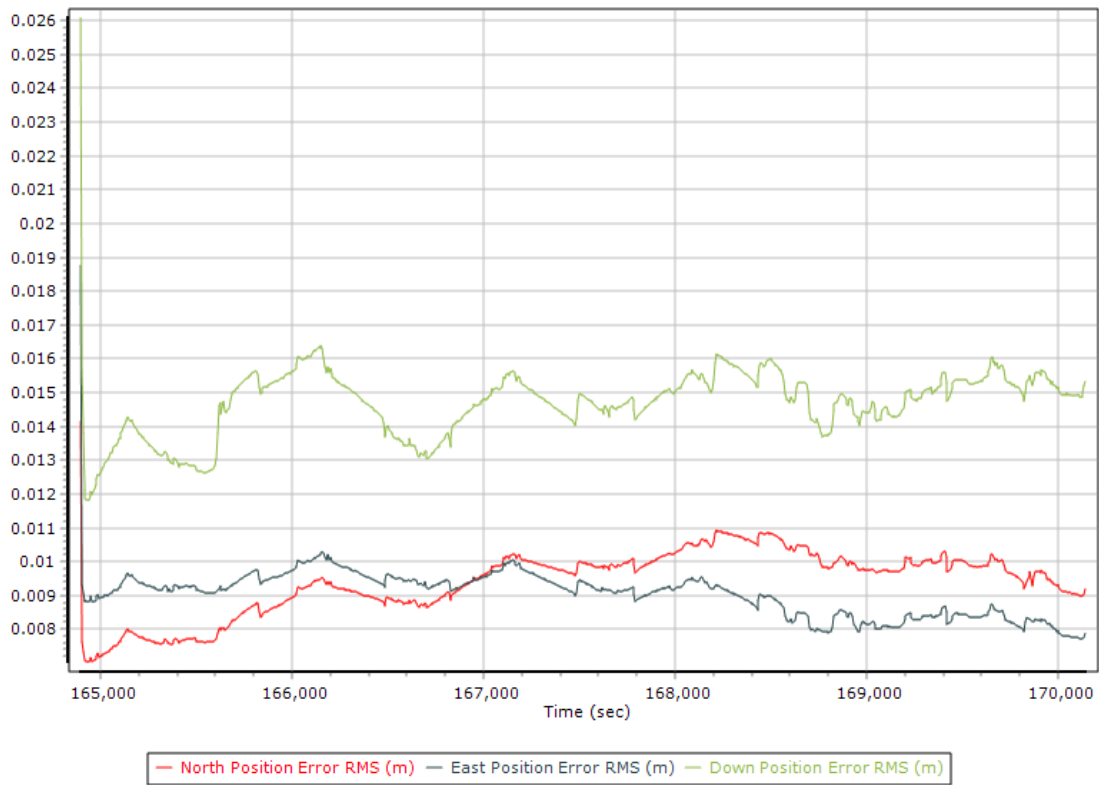
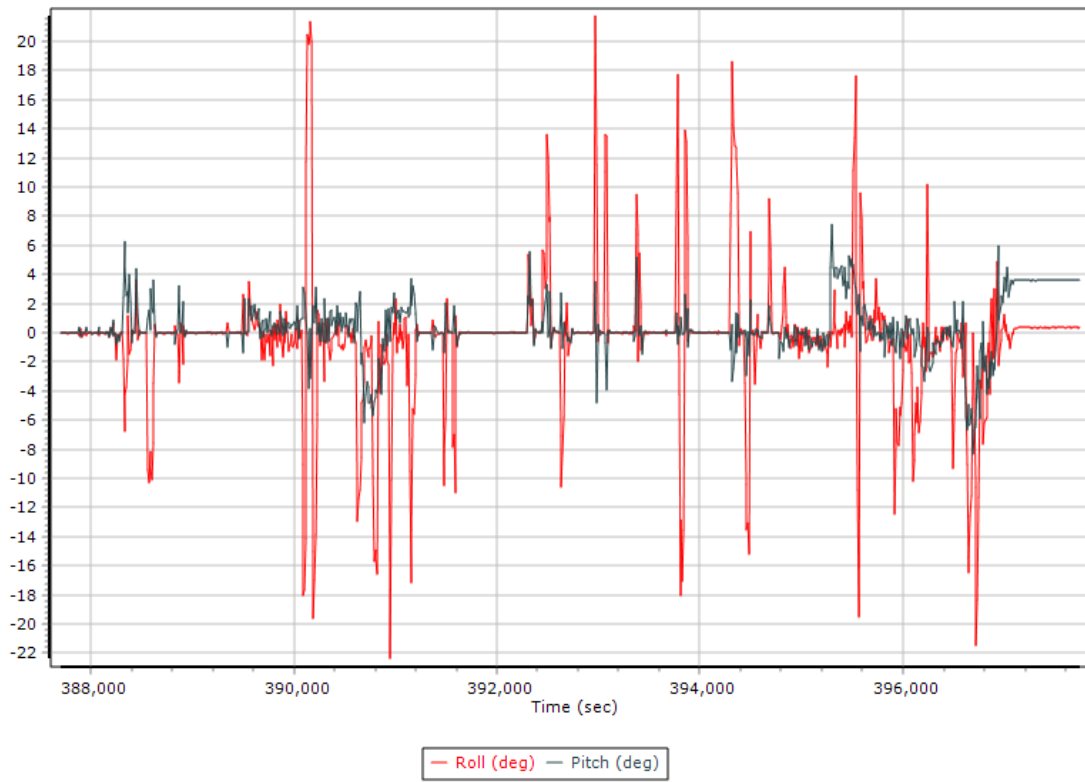
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

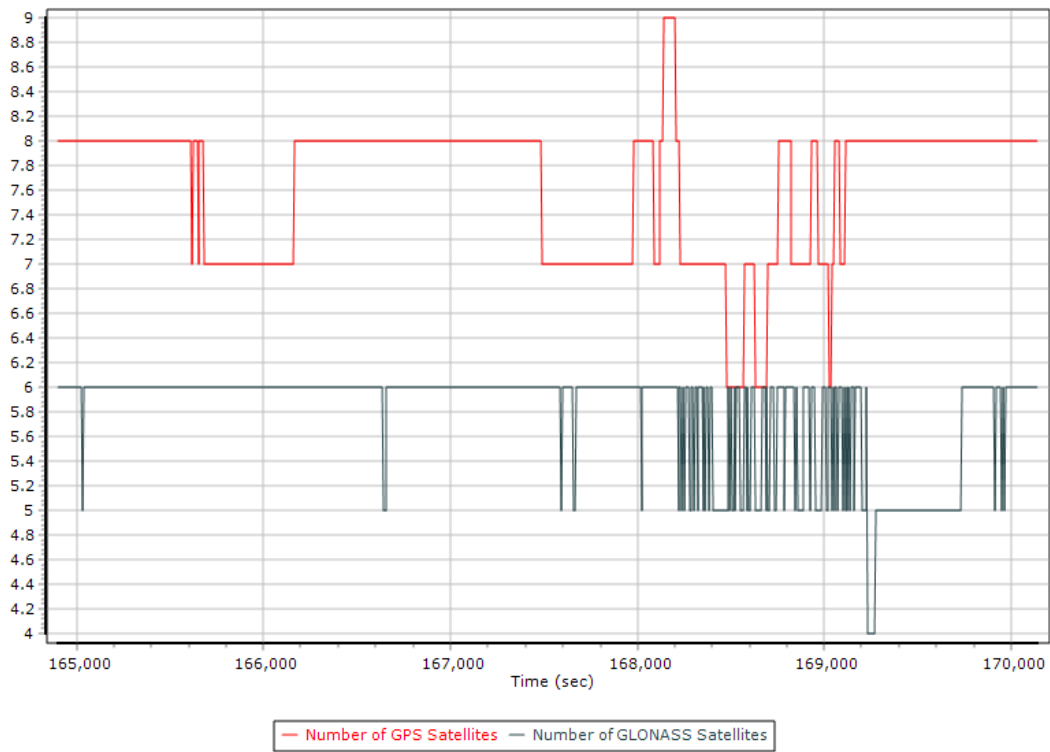
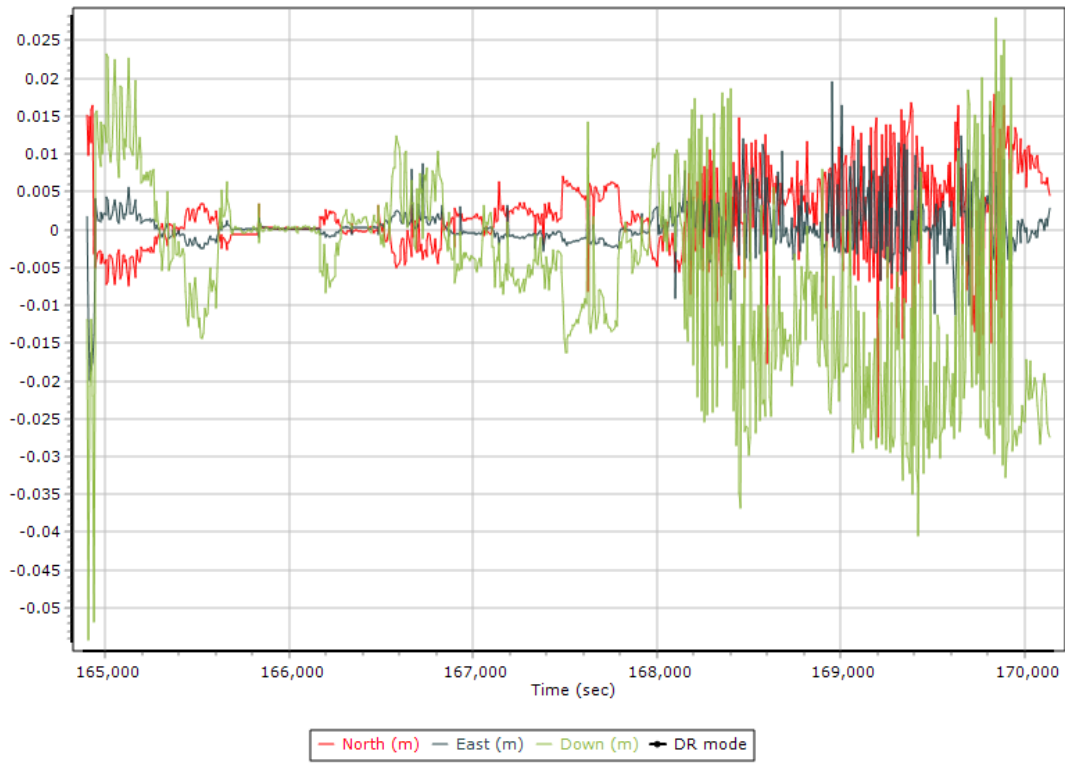
Timing

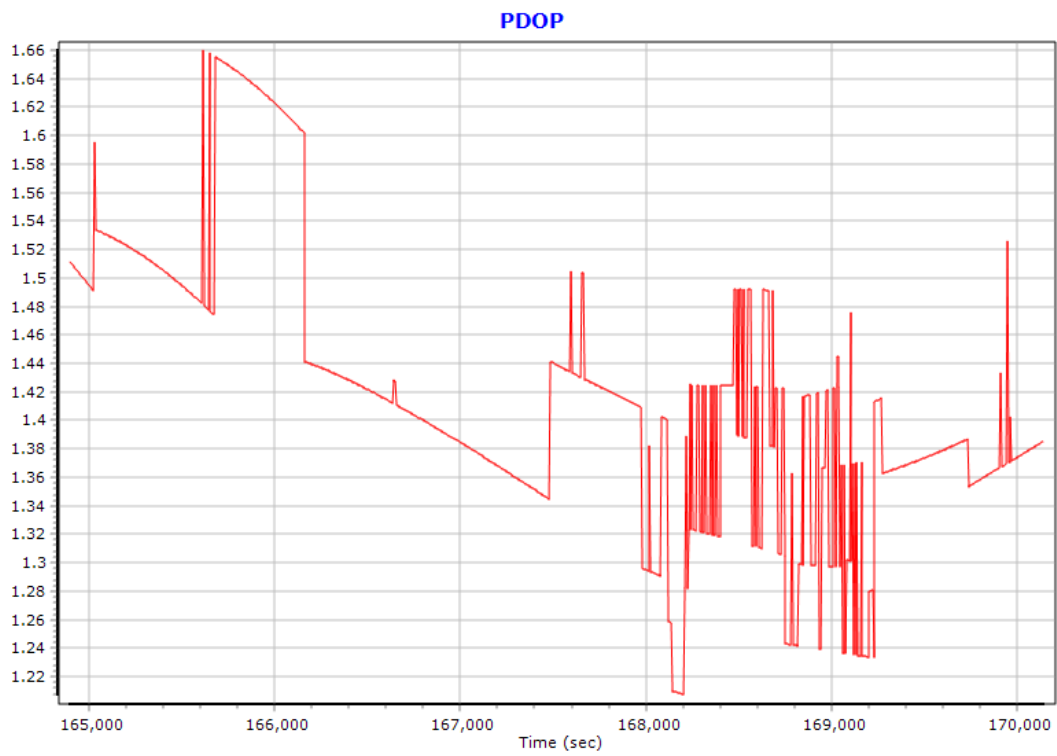
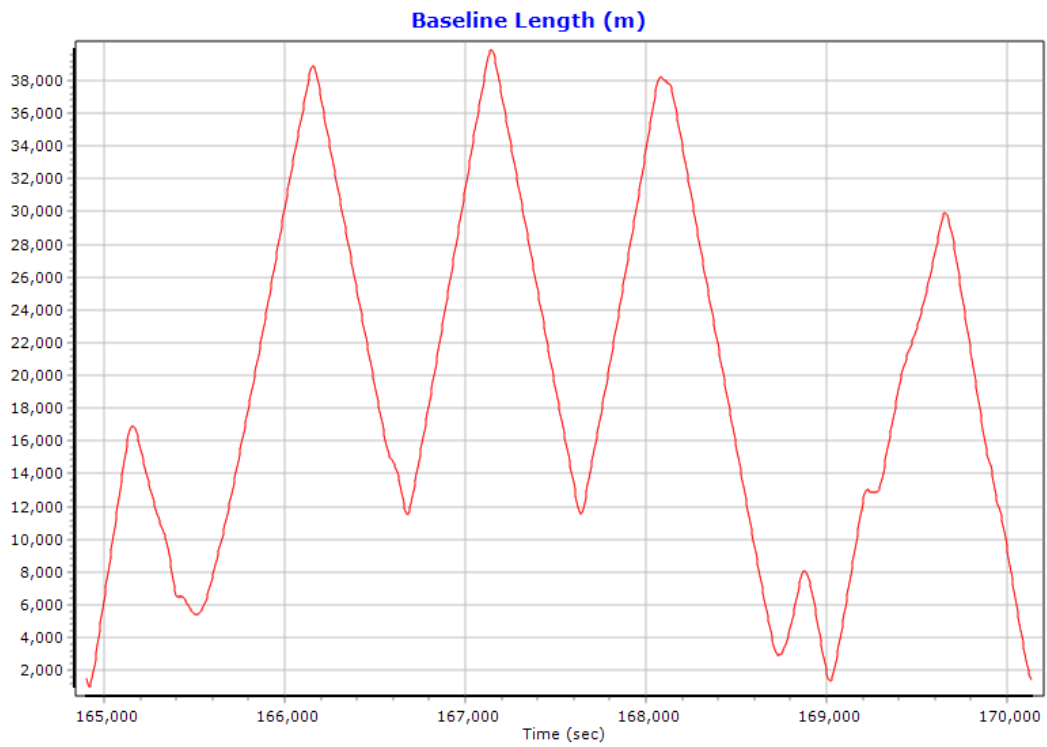
Start	164896.777	Data	Incr. (sec)
End	170146.801	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

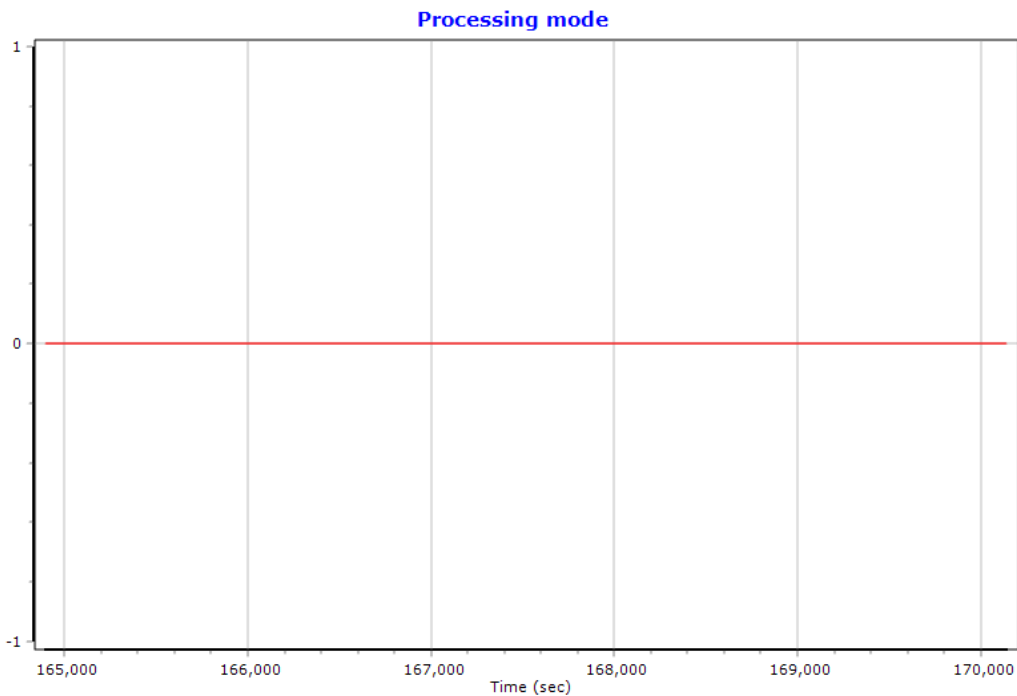
UTC Offset





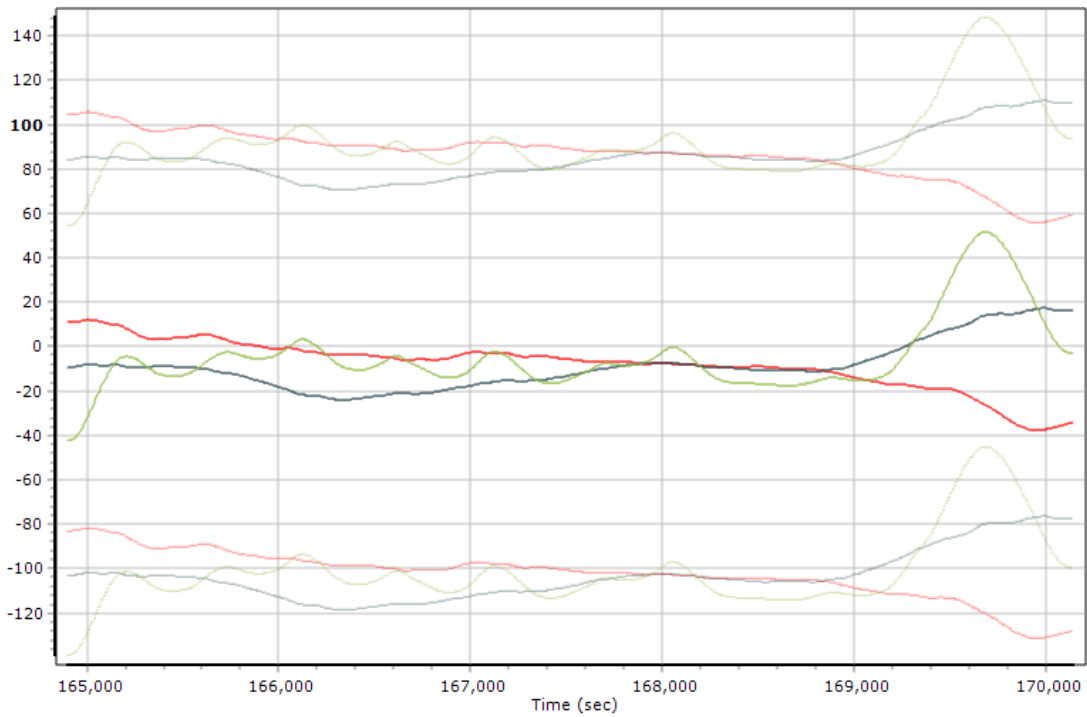




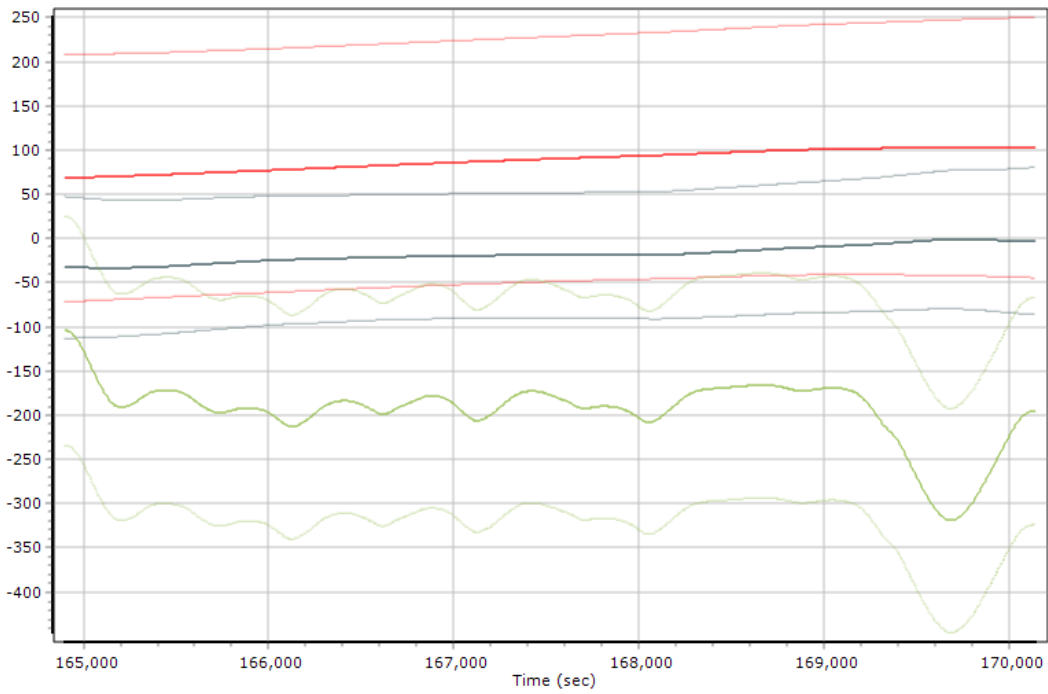


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

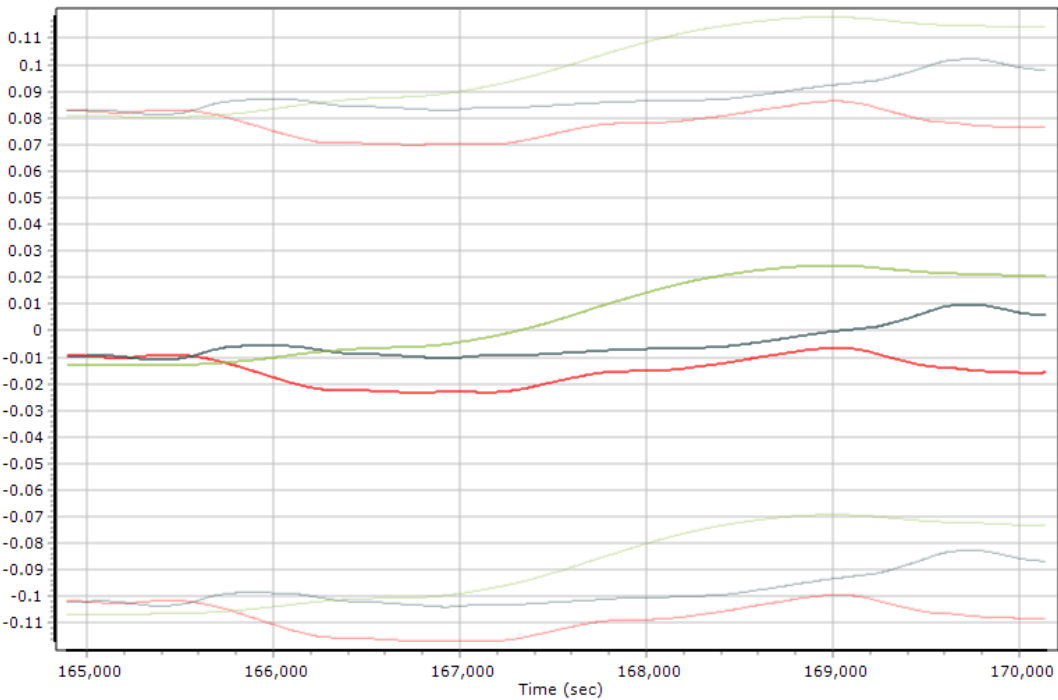
Sensor Errors



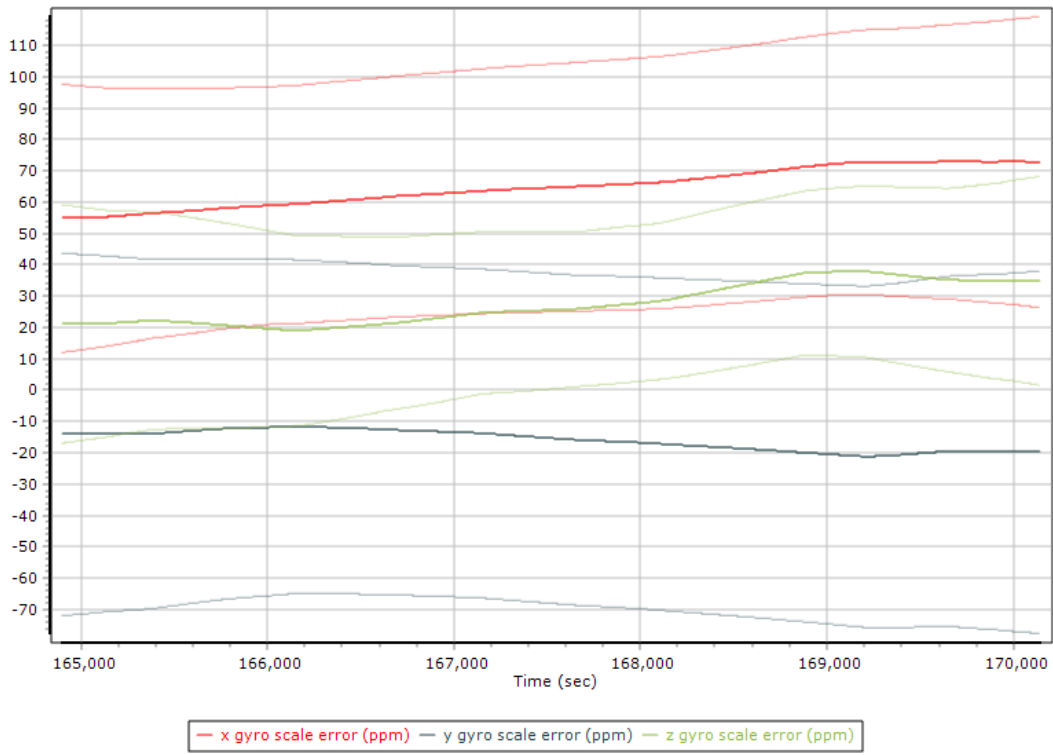
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



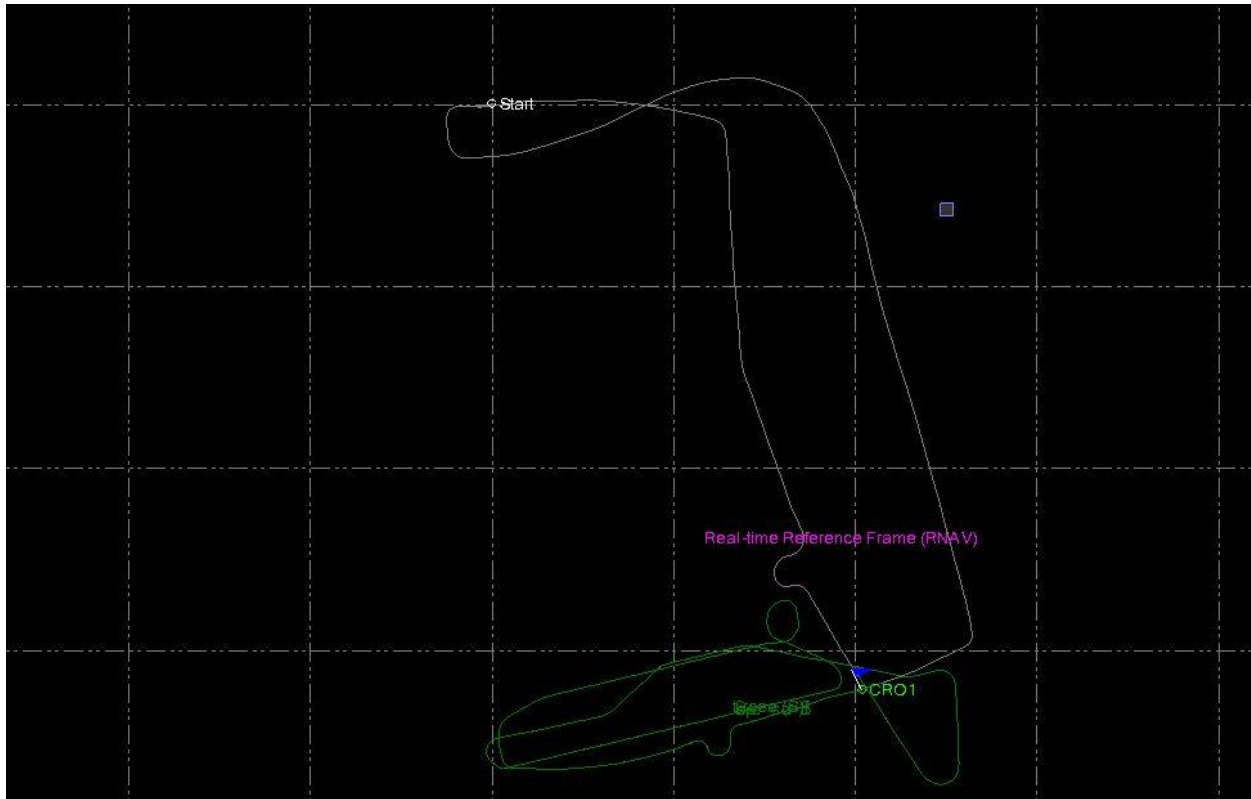
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

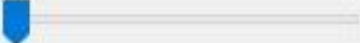


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



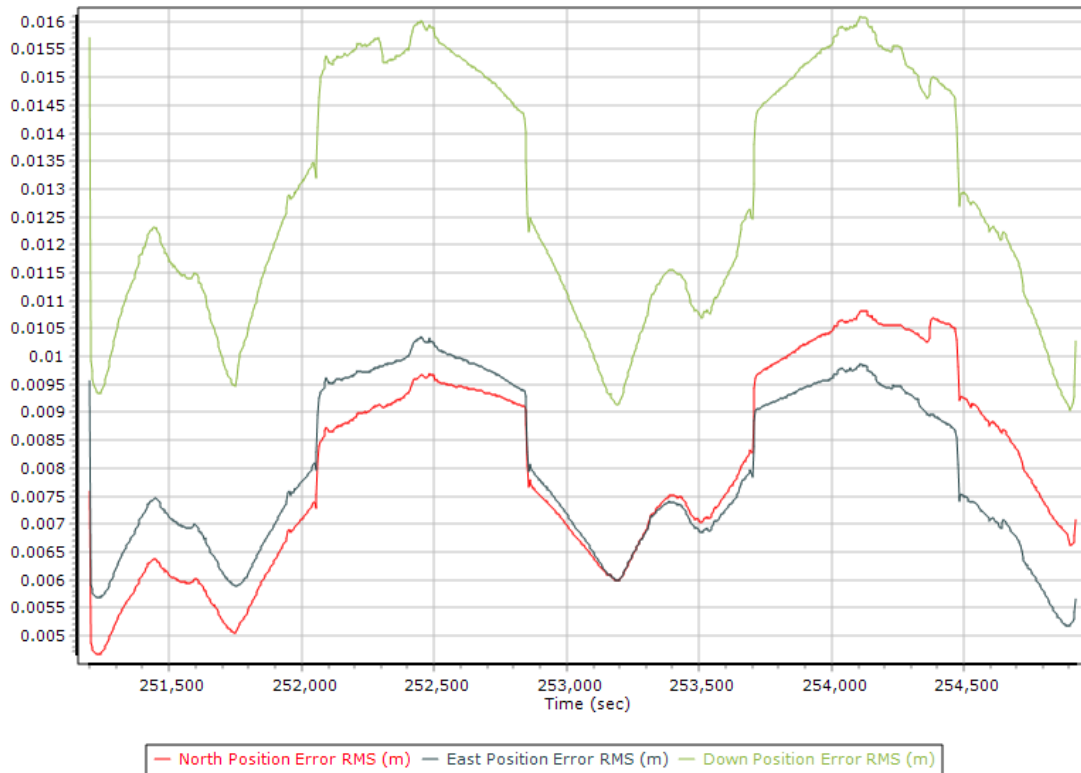
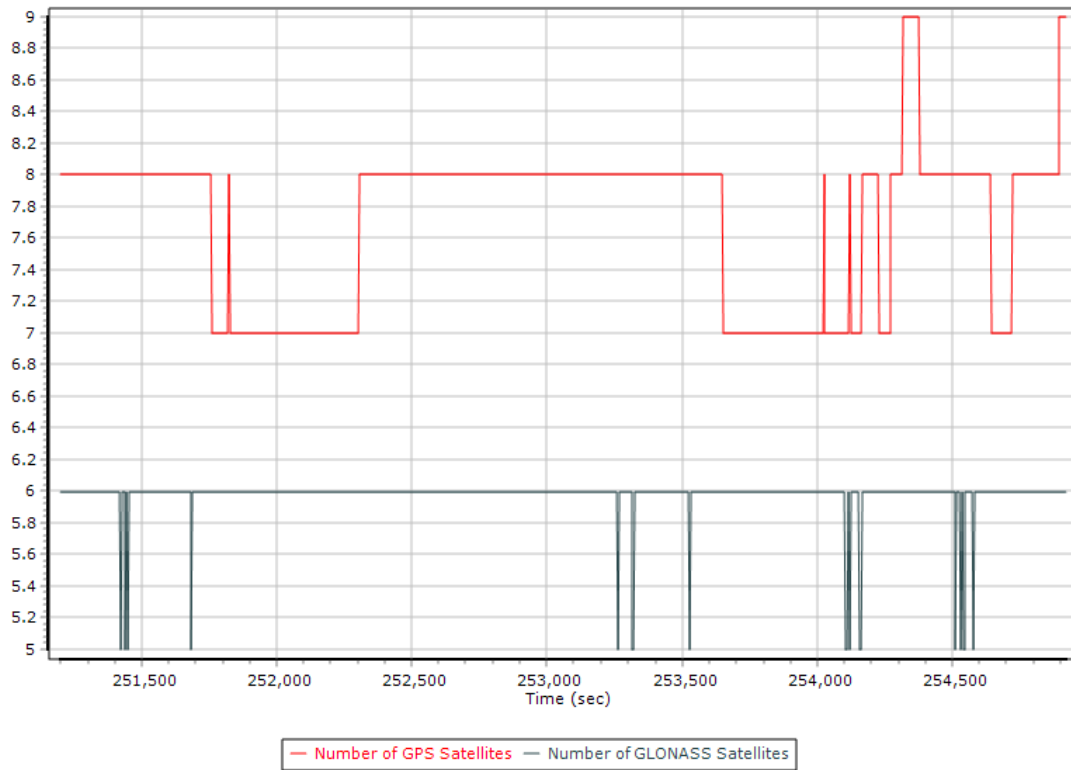
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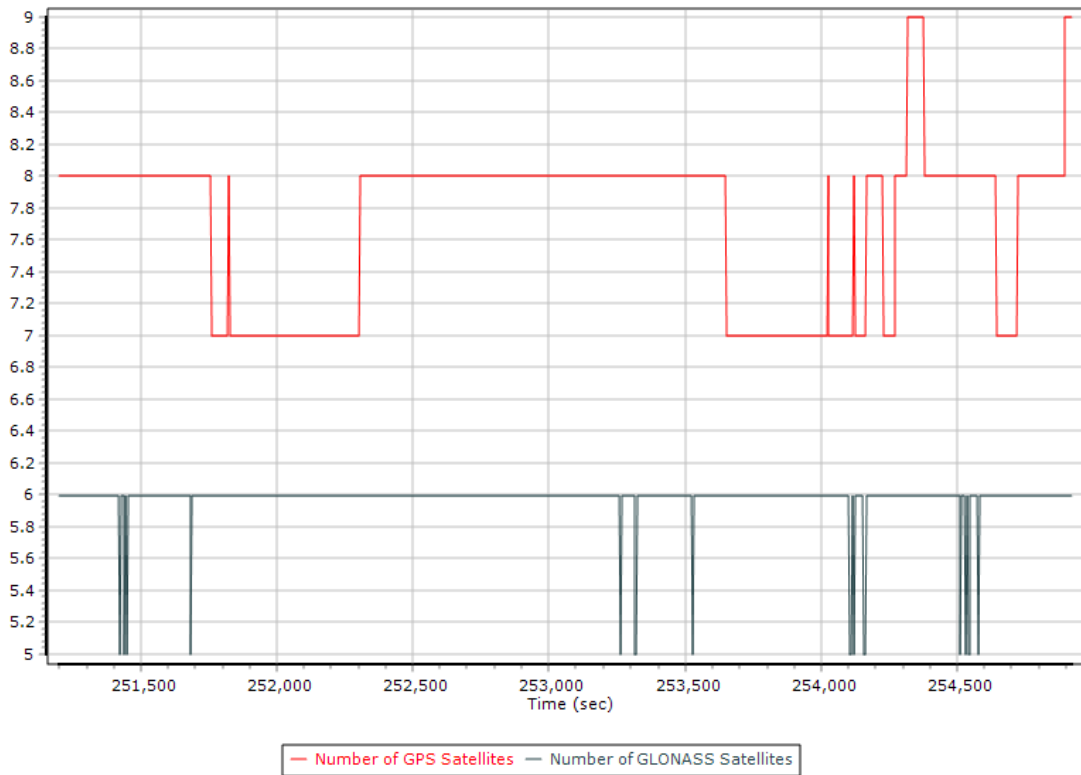
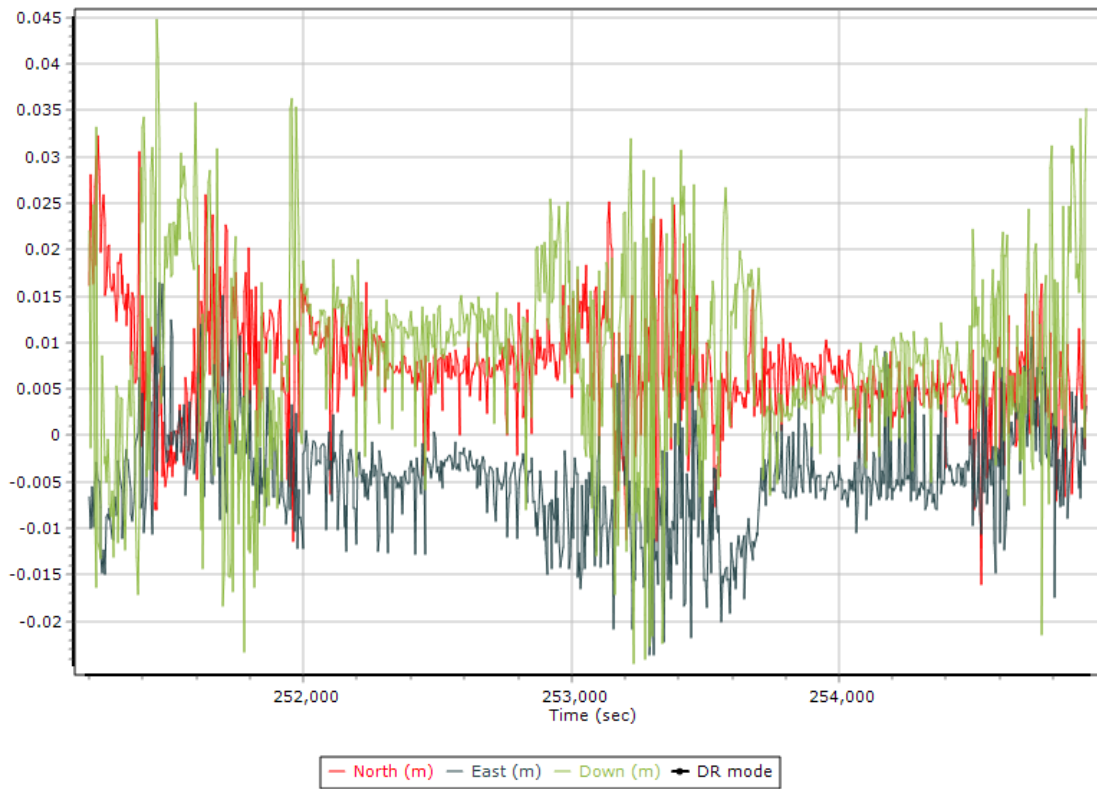


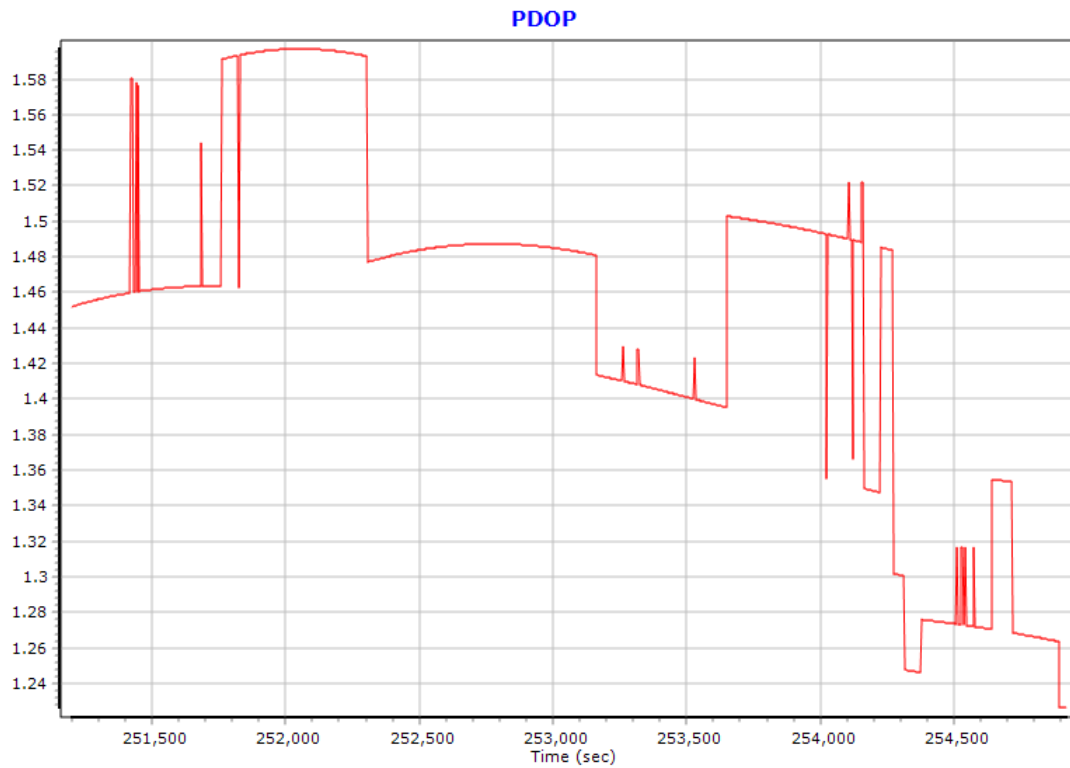
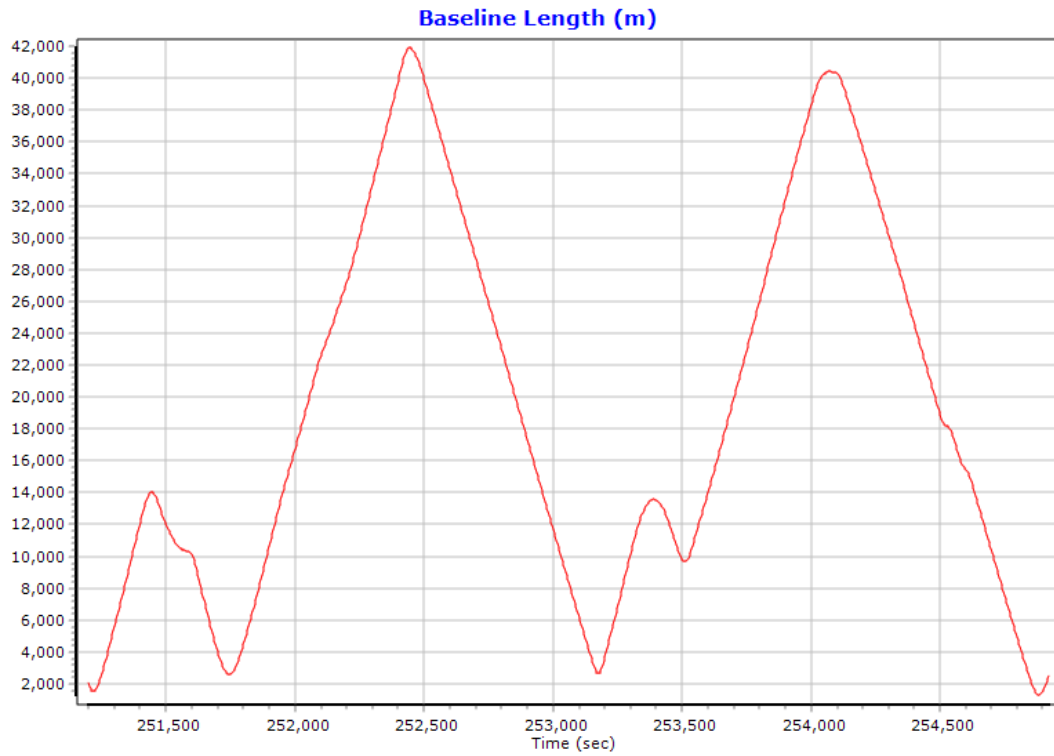
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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="radio"/> <3cm <input type="radio"/> 10cm <input type="radio"/> 50cm <input type="radio"/> 1m <input type="radio"/> 10m		

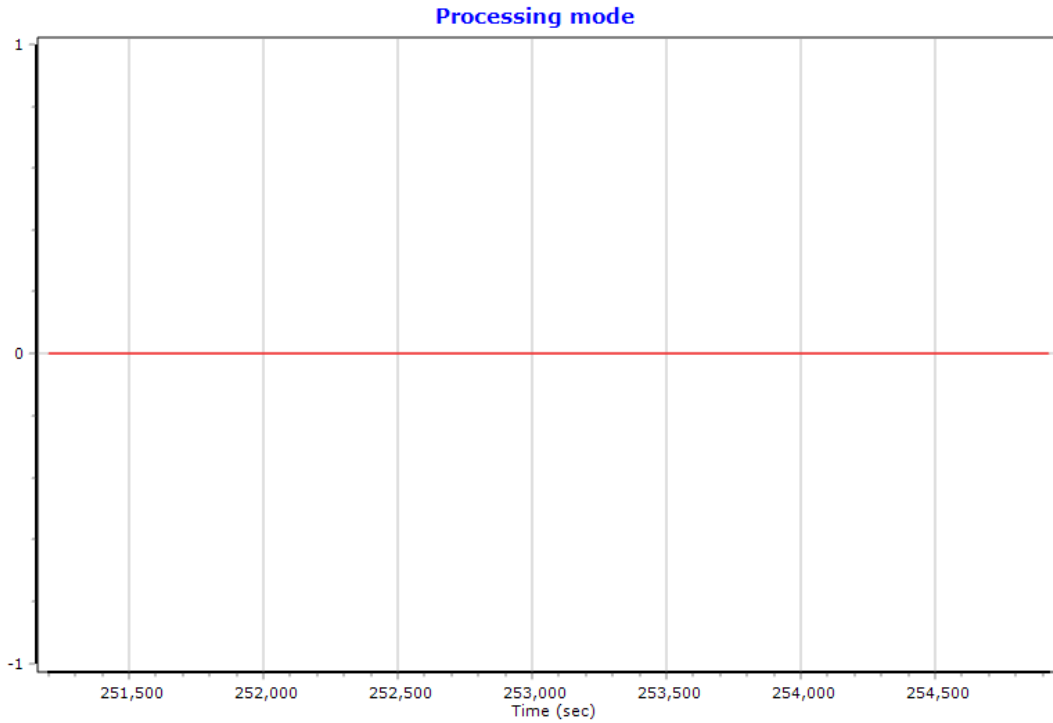
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

Timing										
Start	<input type="text" value="251197.649"/>									
End	<input type="text" value="254924.378"/>									
<input type="checkbox"/> Entire time interval <input checked="" type="checkbox"/> Seconds of start week										
UTC Offset	<input type="text" value="18.000"/>									
	<table border="1"> <thead> <tr> <th>Data</th> <th>Incr. (sec)</th> </tr> </thead> <tbody> <tr> <td>Output Record</td> <td>0.005000</td> </tr> <tr> <td>IMU</td> <td>0.005000</td> </tr> <tr> <td>Primary GNSS</td> <td>1.000000</td> </tr> </tbody> </table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000	
Data	Incr. (sec)									
Output Record	0.005000									
IMU	0.005000									
Primary GNSS	1.000000									



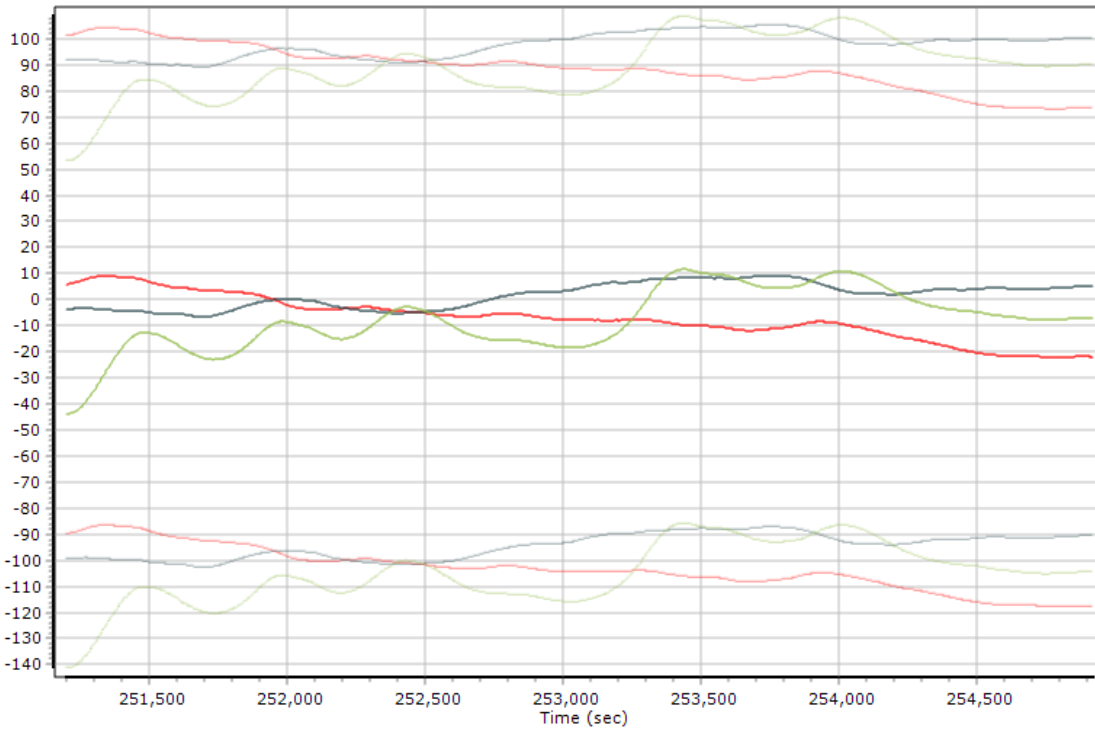




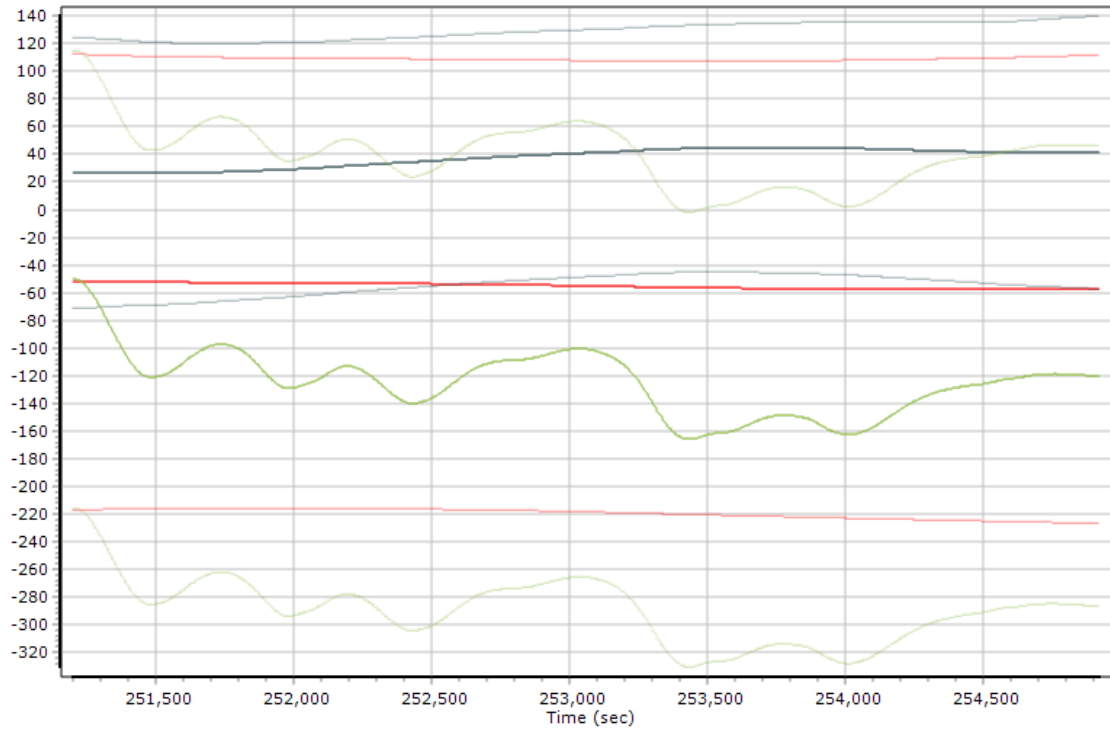


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

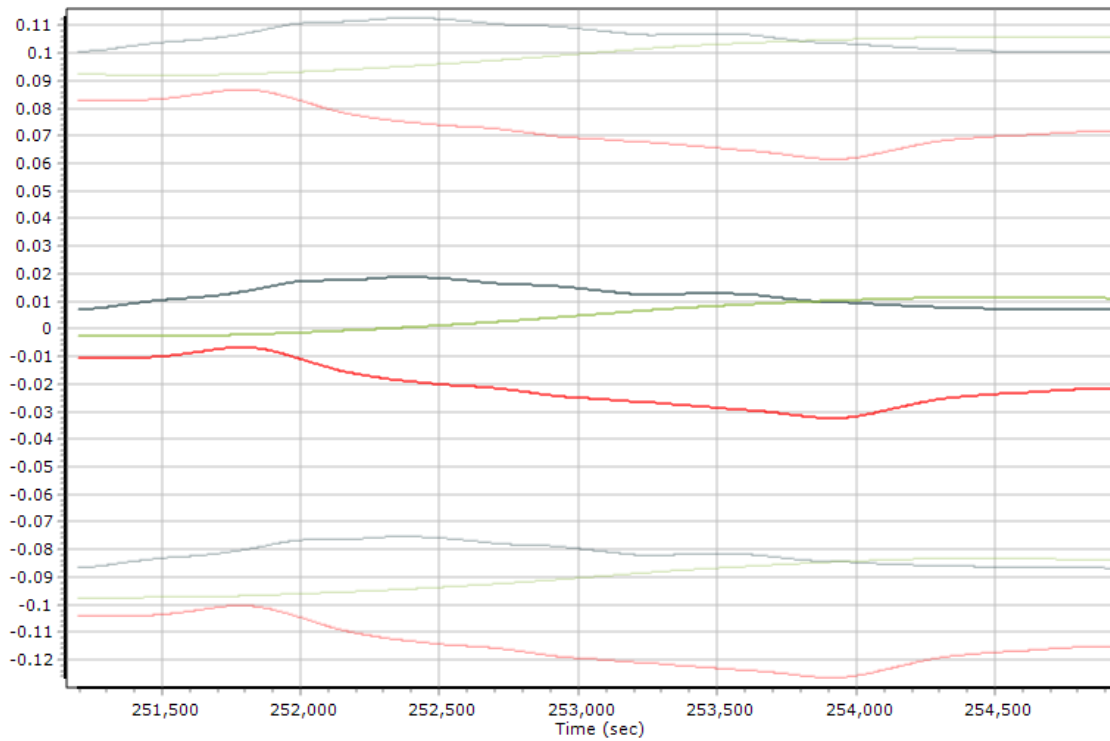
Sensor Errors



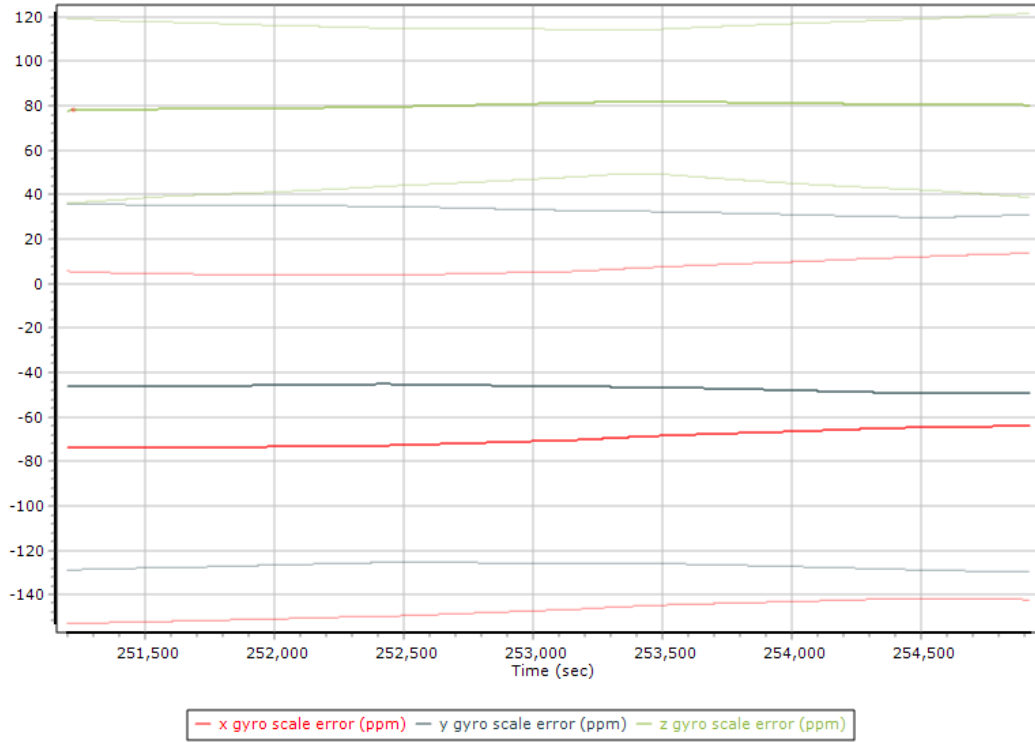
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



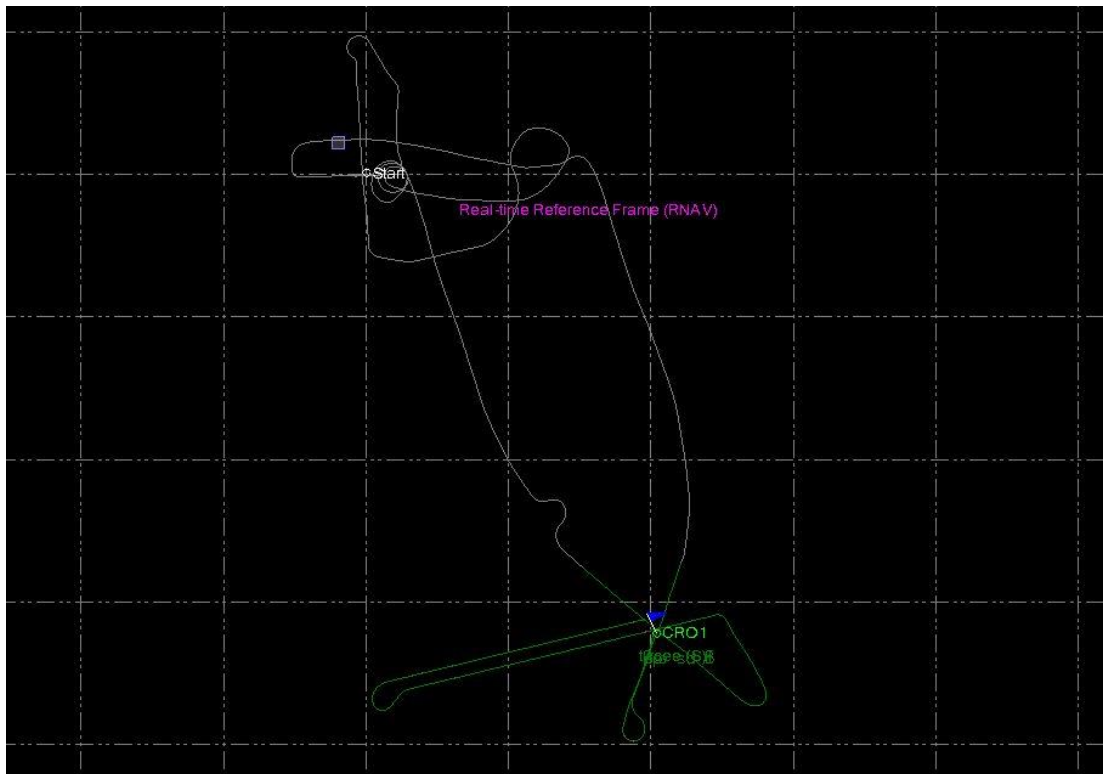
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



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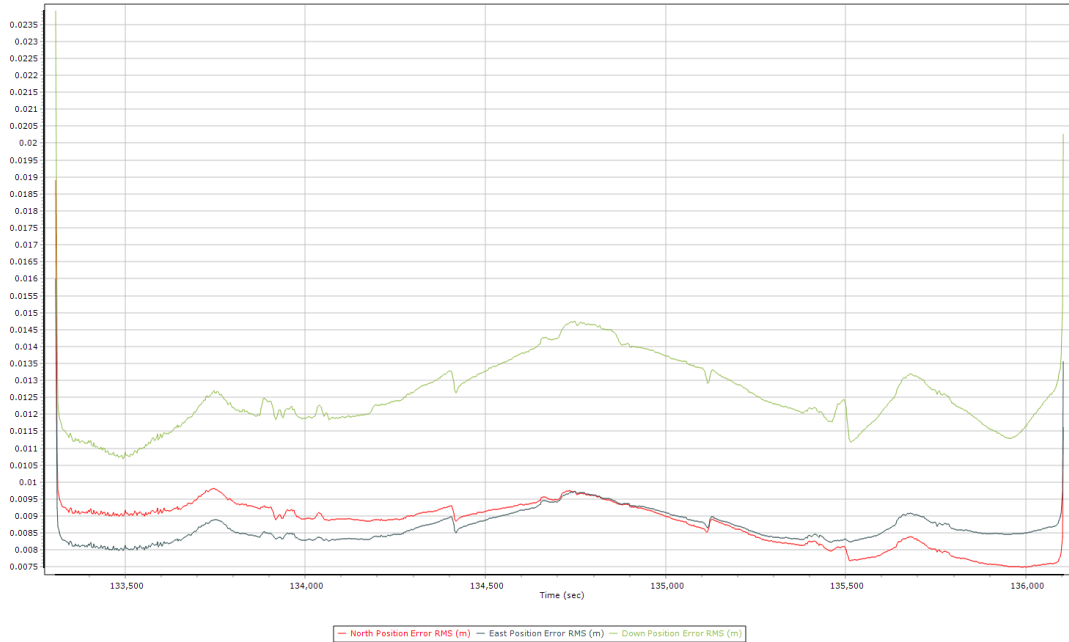
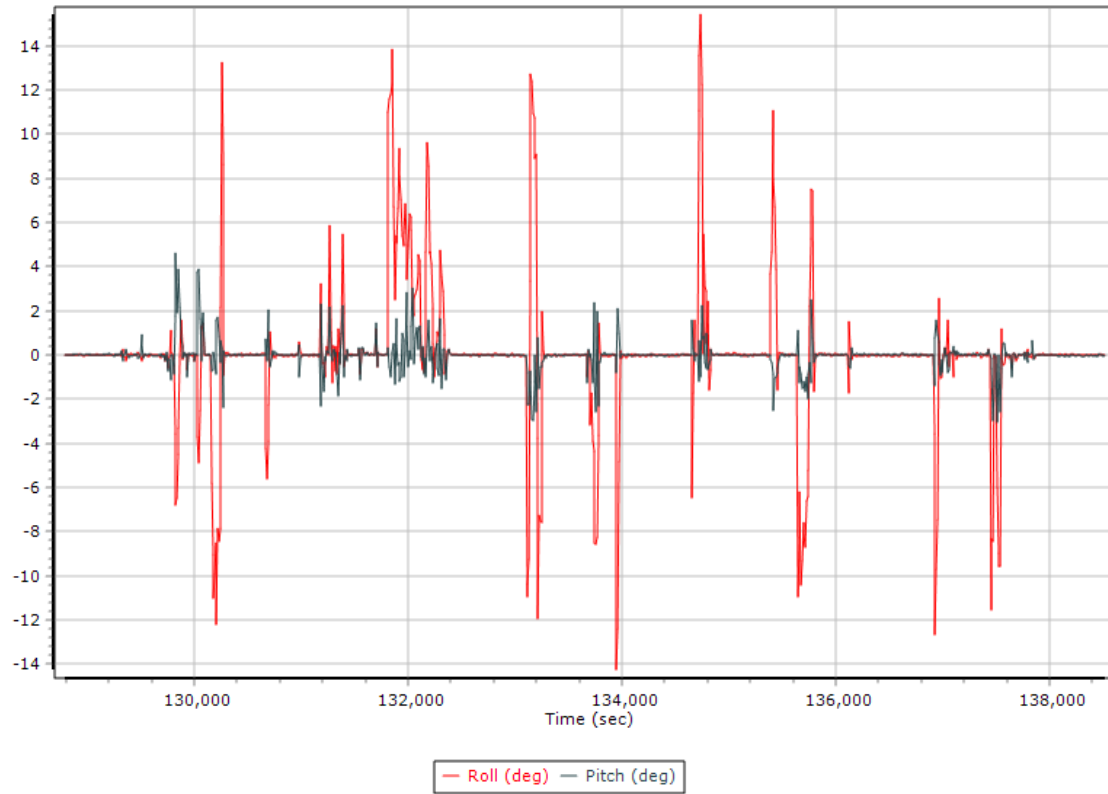


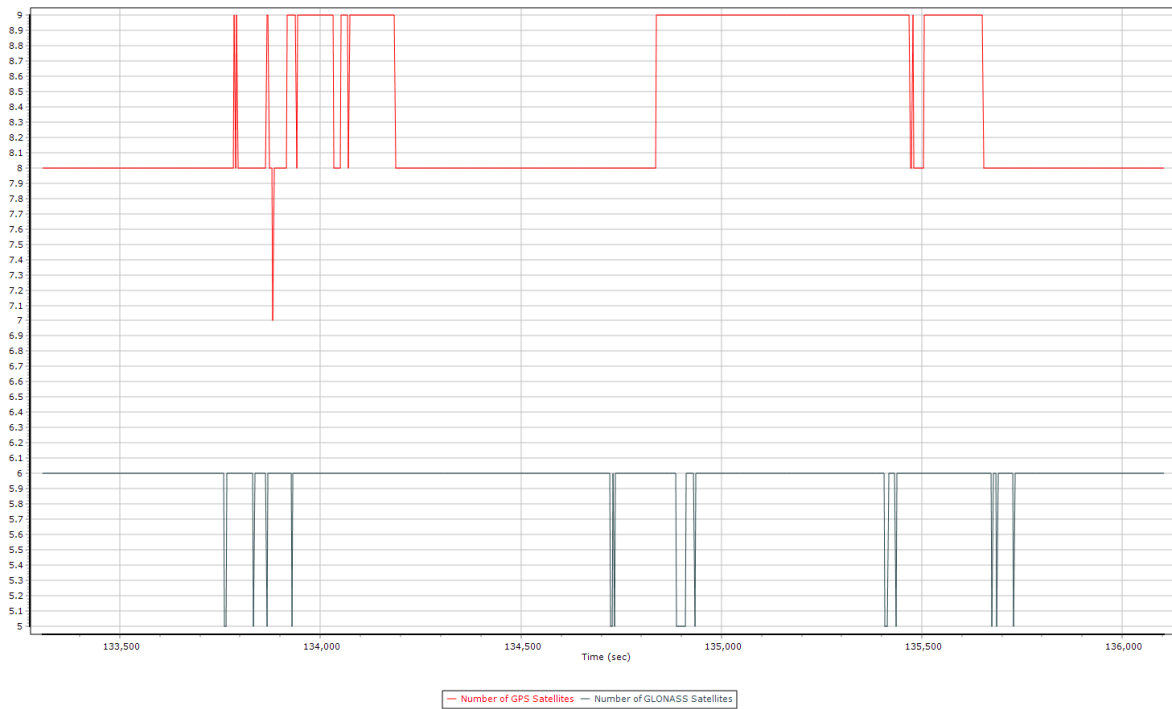
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	-0.034 m	X	0.000 deg
Y	-0.010 m	Y	0.000 deg
Z	-0.352 m	Z	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm		Aircraft to Stabilized Mount Mounting Angles	
X	-0.049 m	X	0.000 deg
Y	0.003 m	Y	0.000 deg
Z	-1.230 m	Z	0.000 deg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

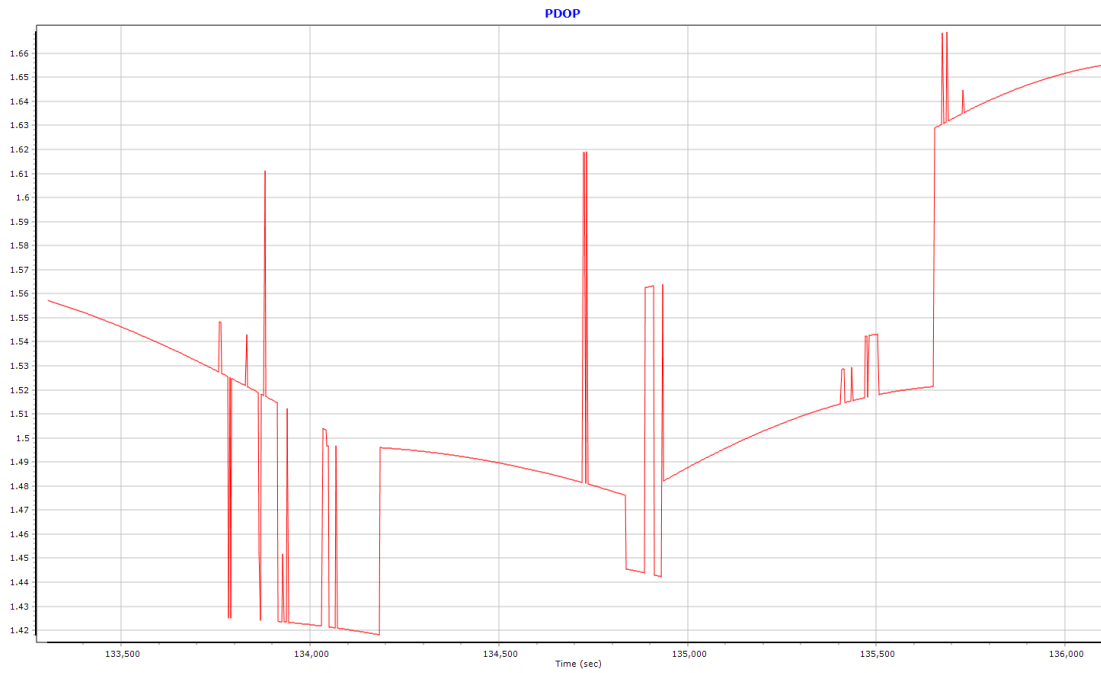
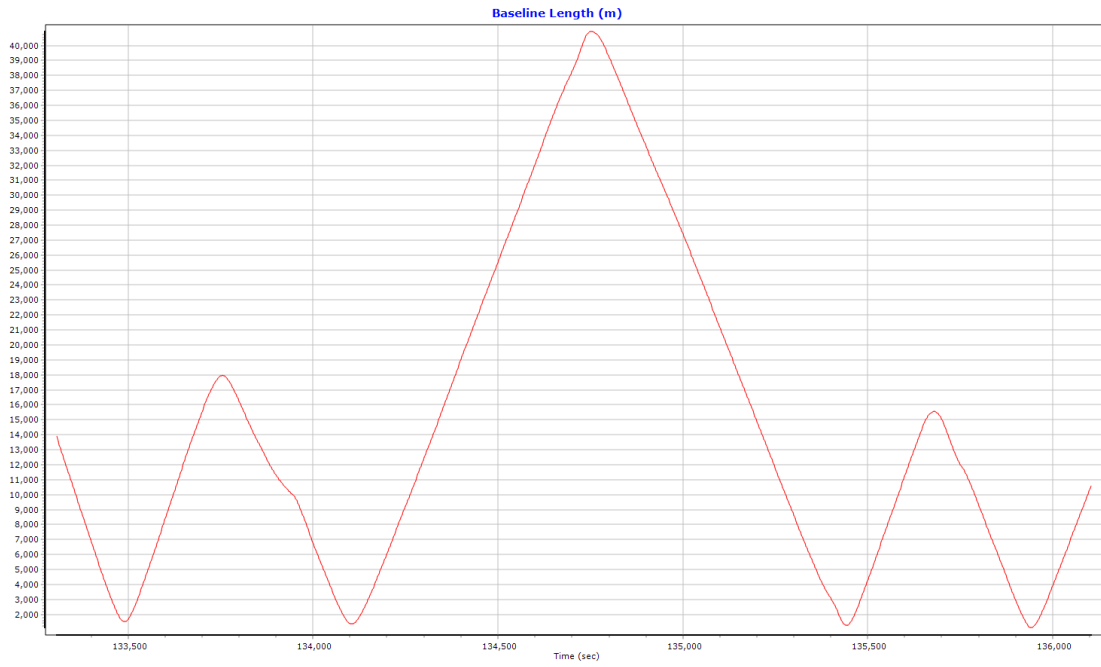
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

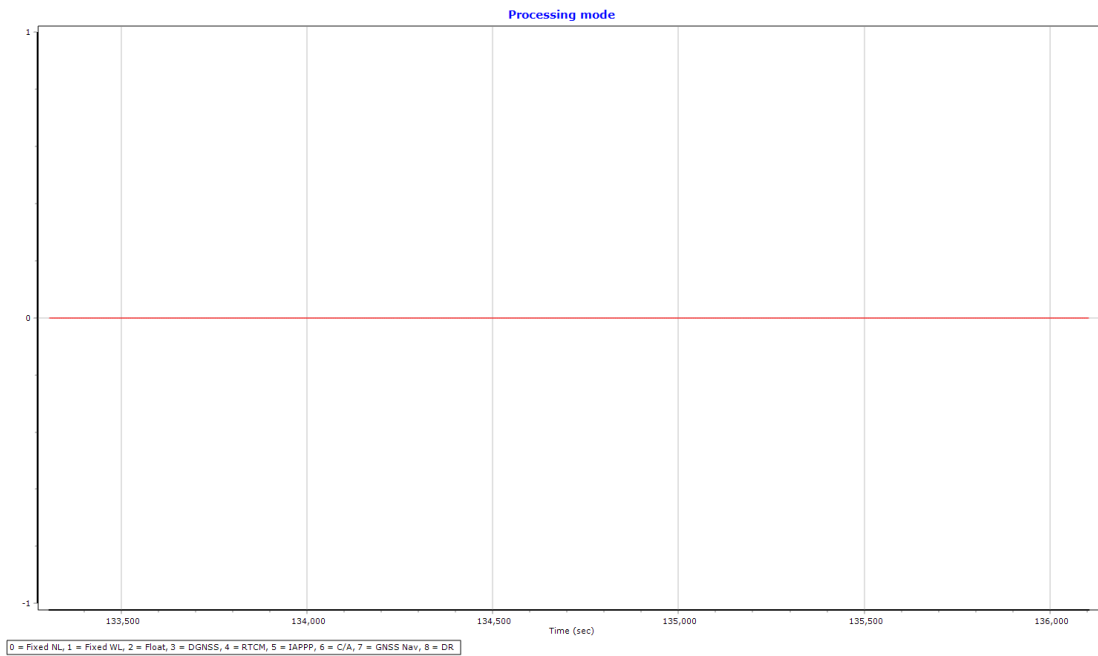
Timing	
Start	133305.684
End	136105.227
<input type="checkbox"/> Entire time interval	
<input checked="" type="checkbox"/> Seconds of start week	
UTC Offset	18.000
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



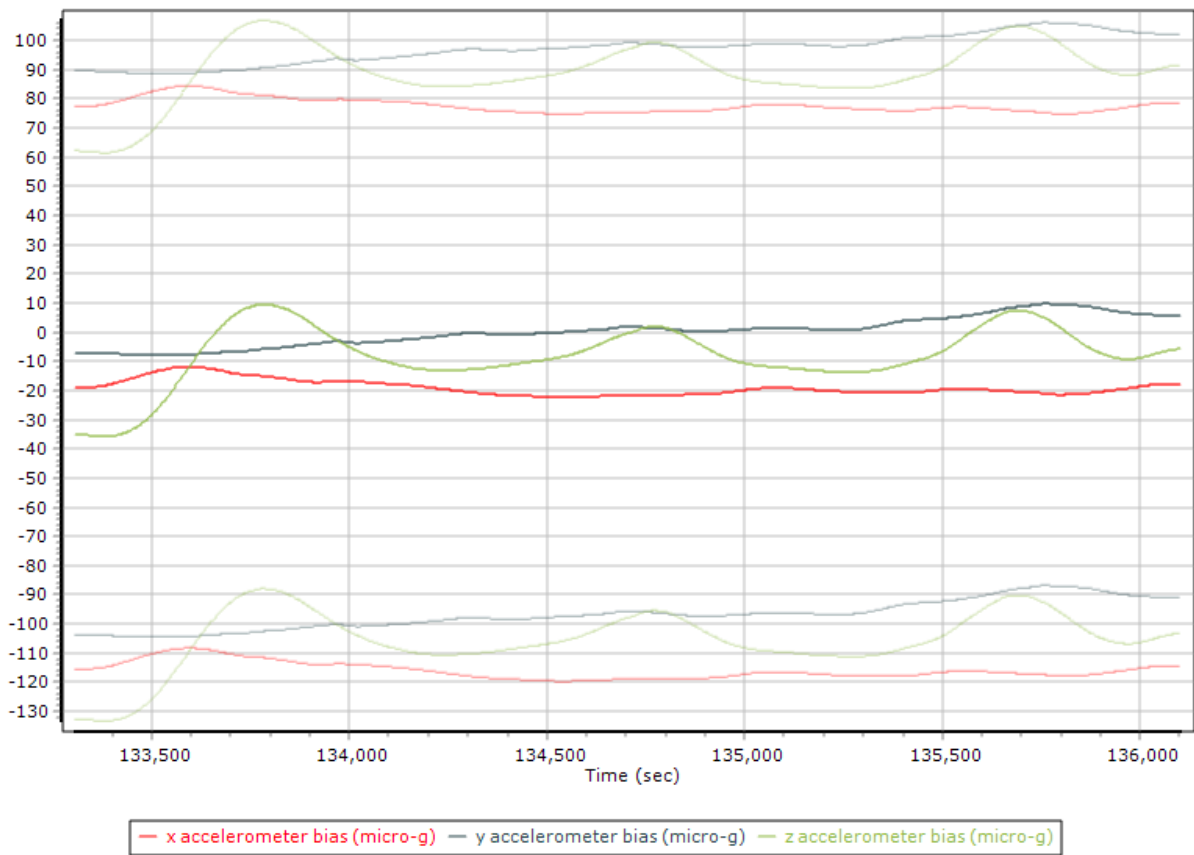


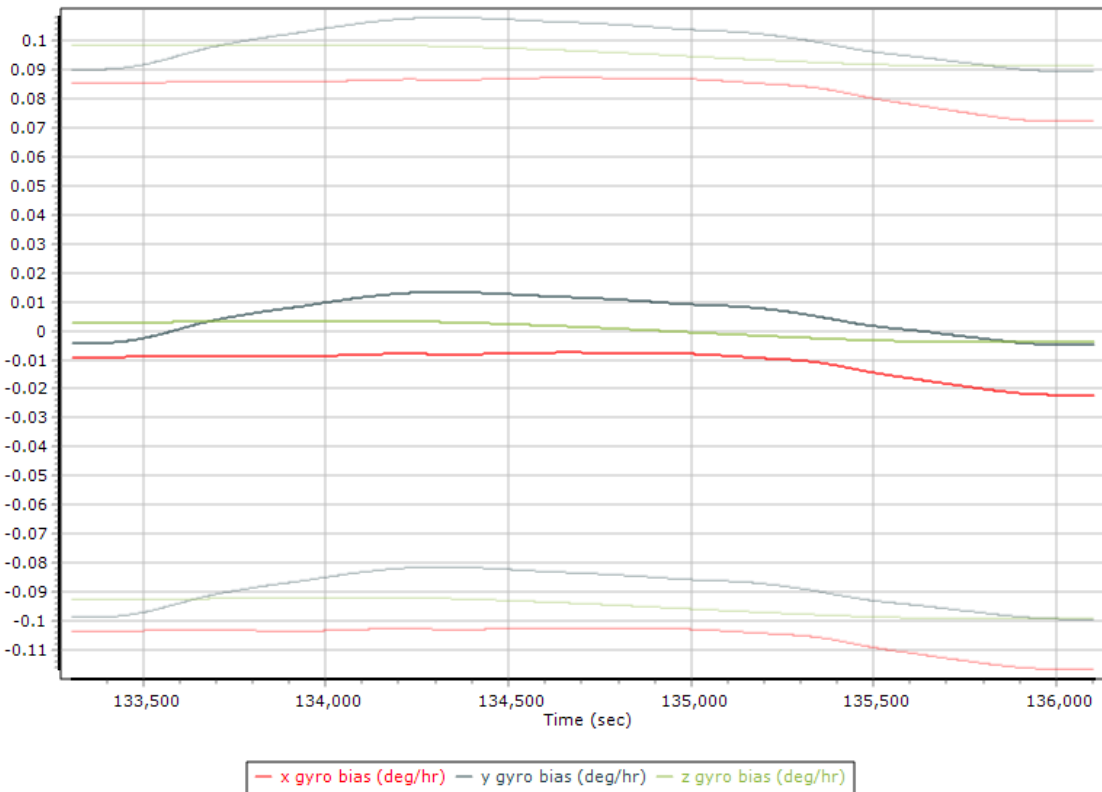
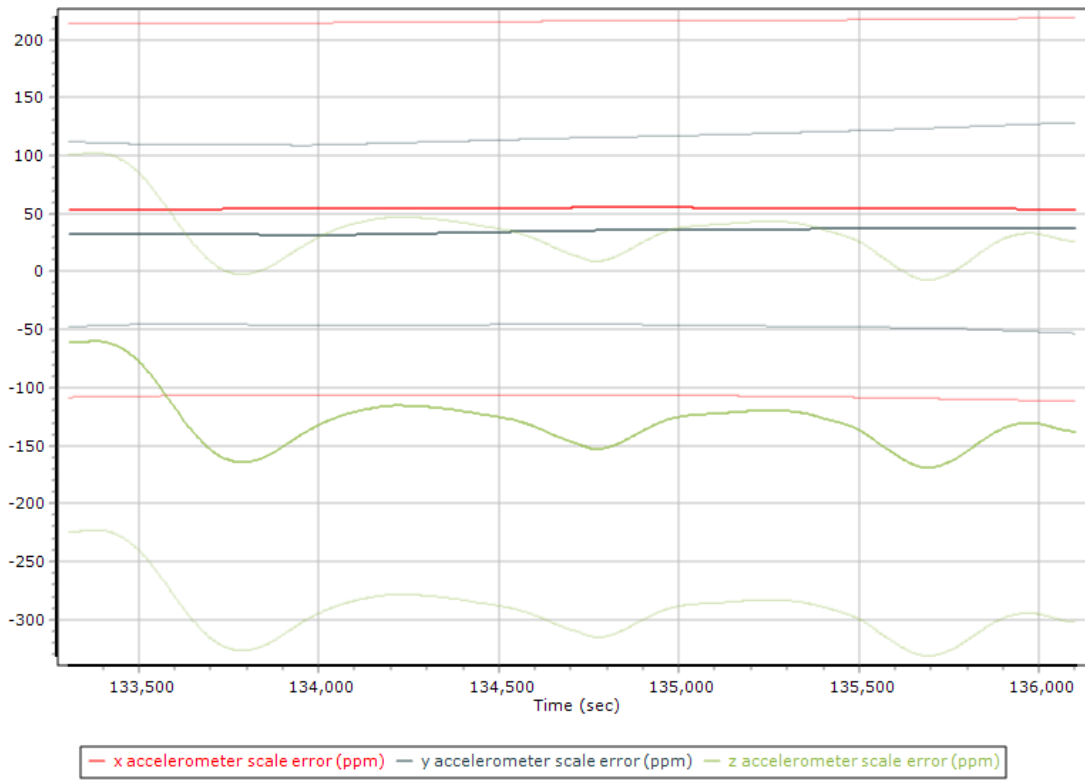


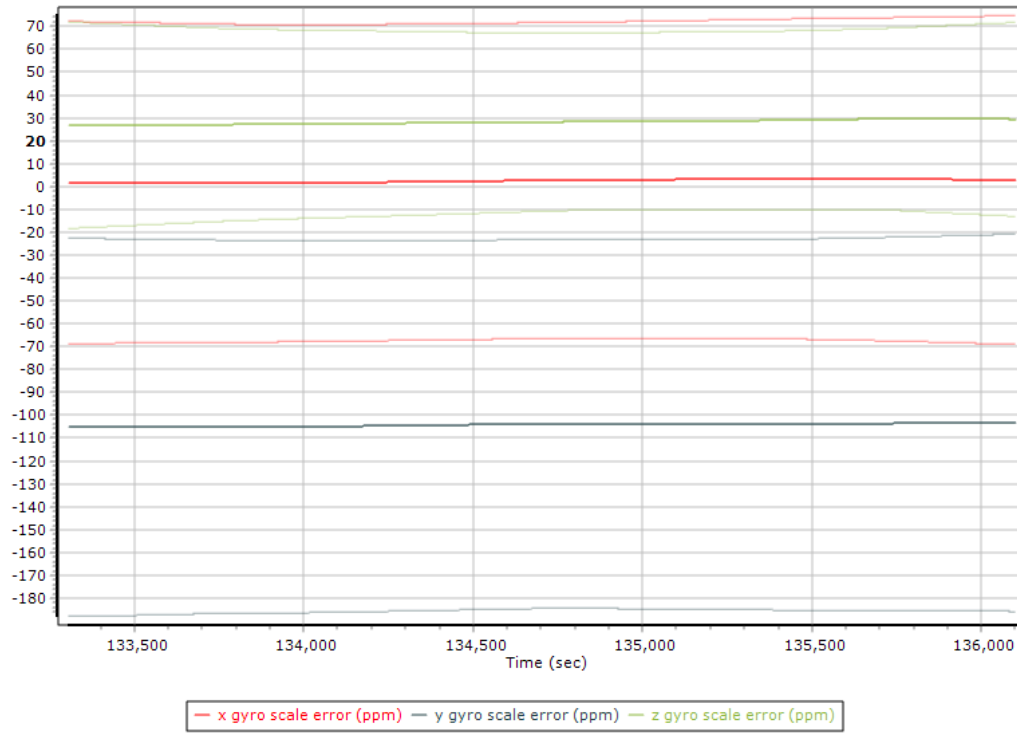




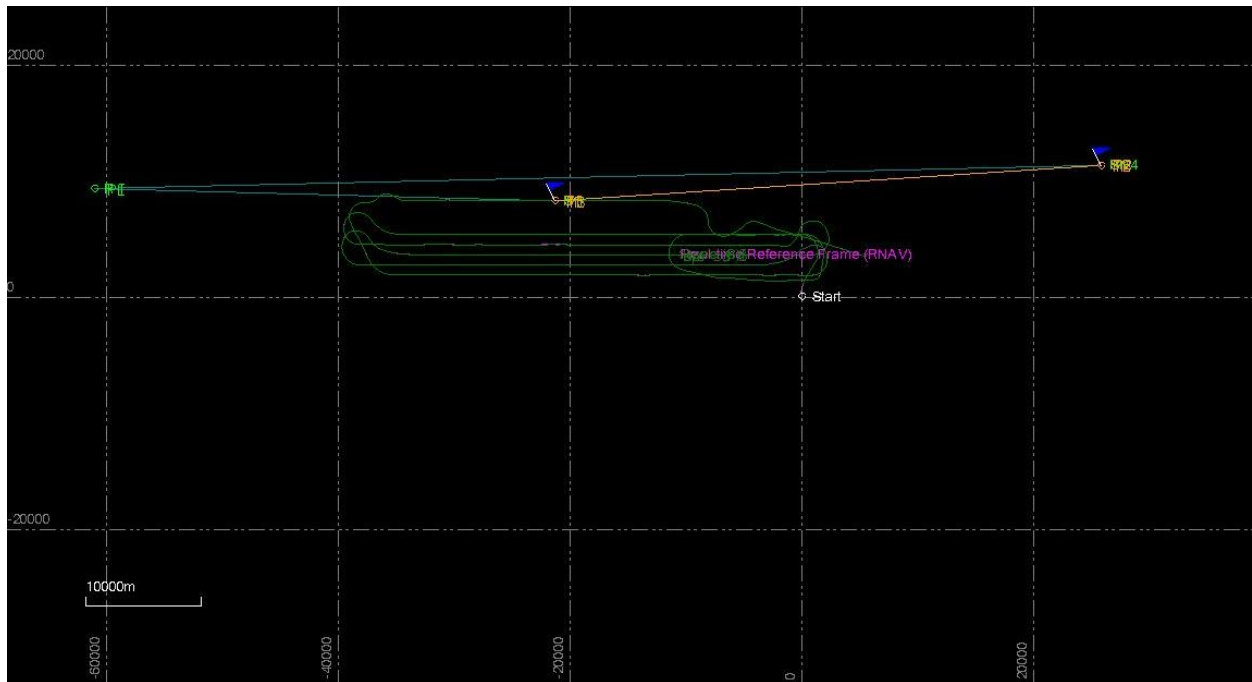
Sensor Errors

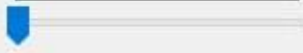




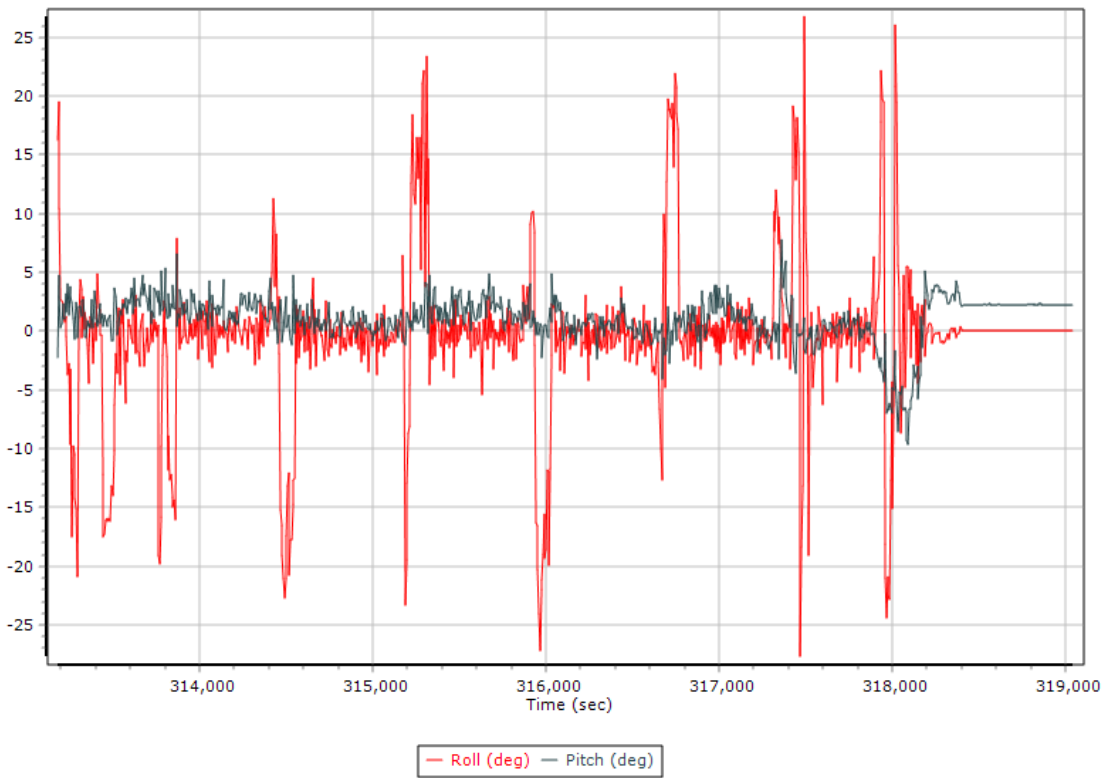
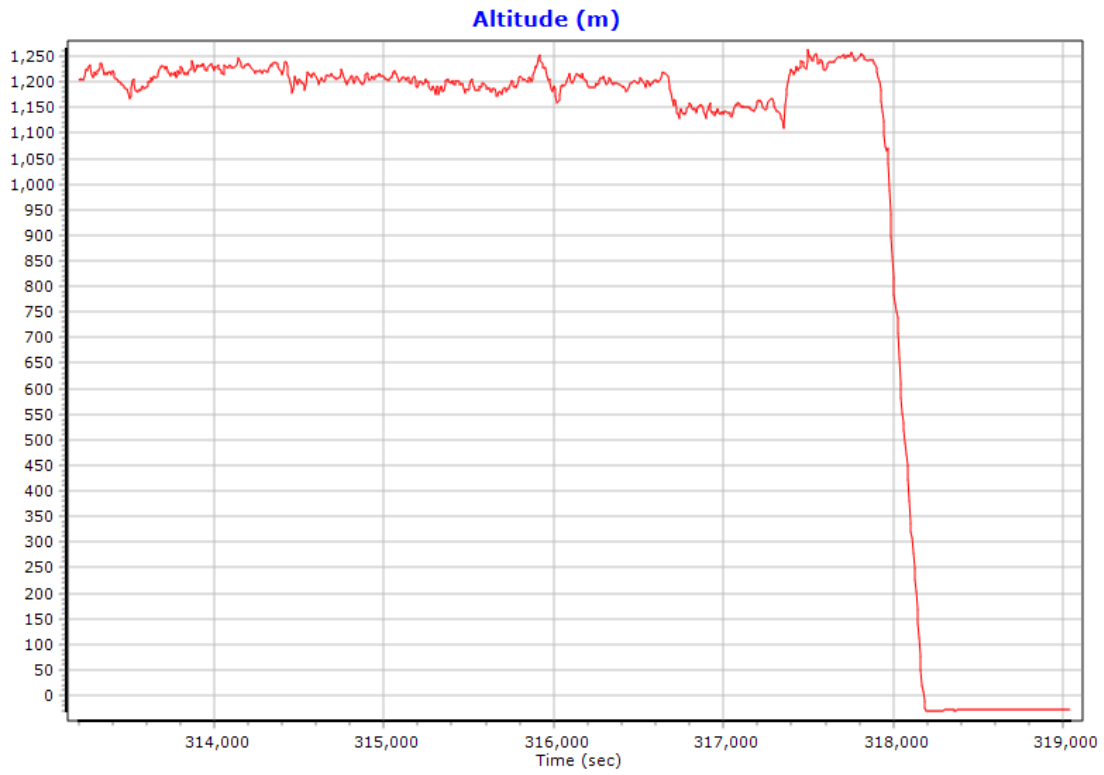


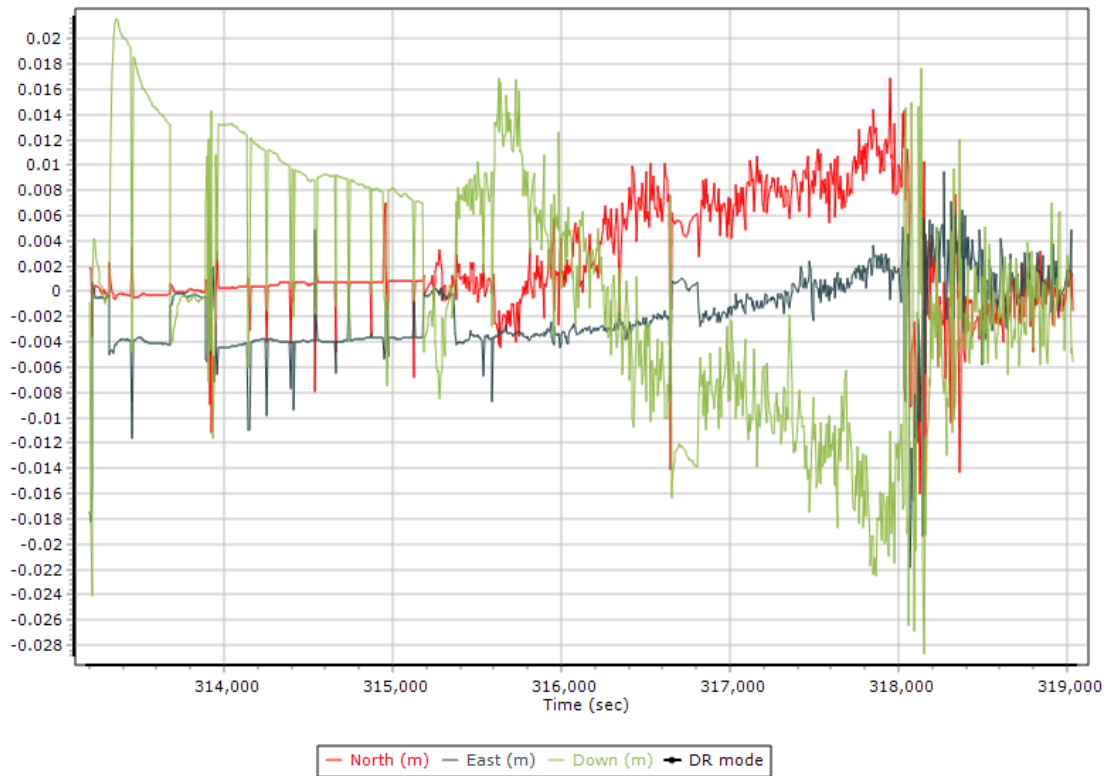
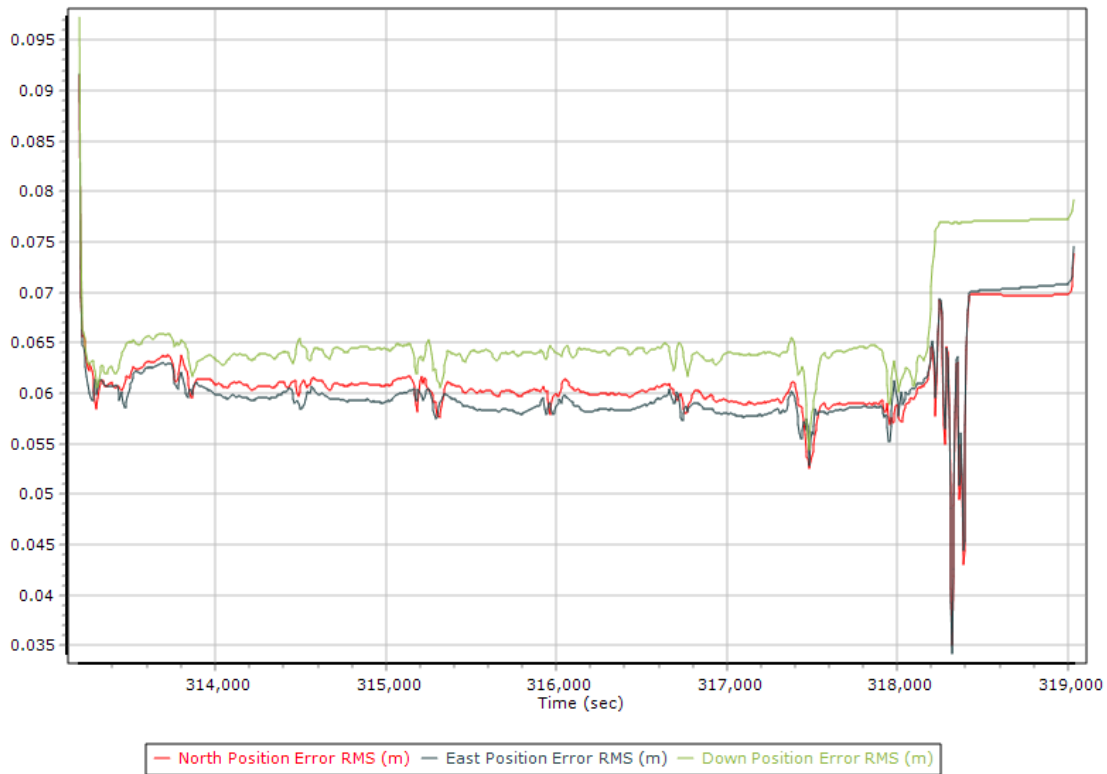
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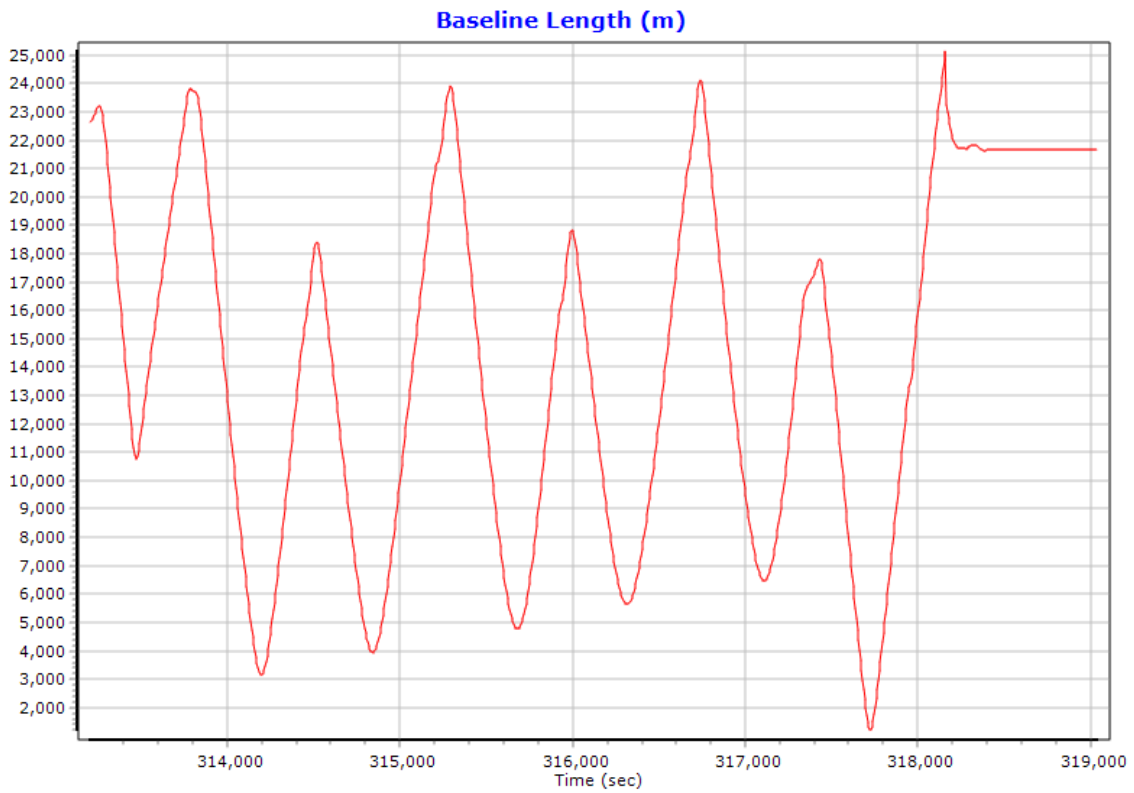
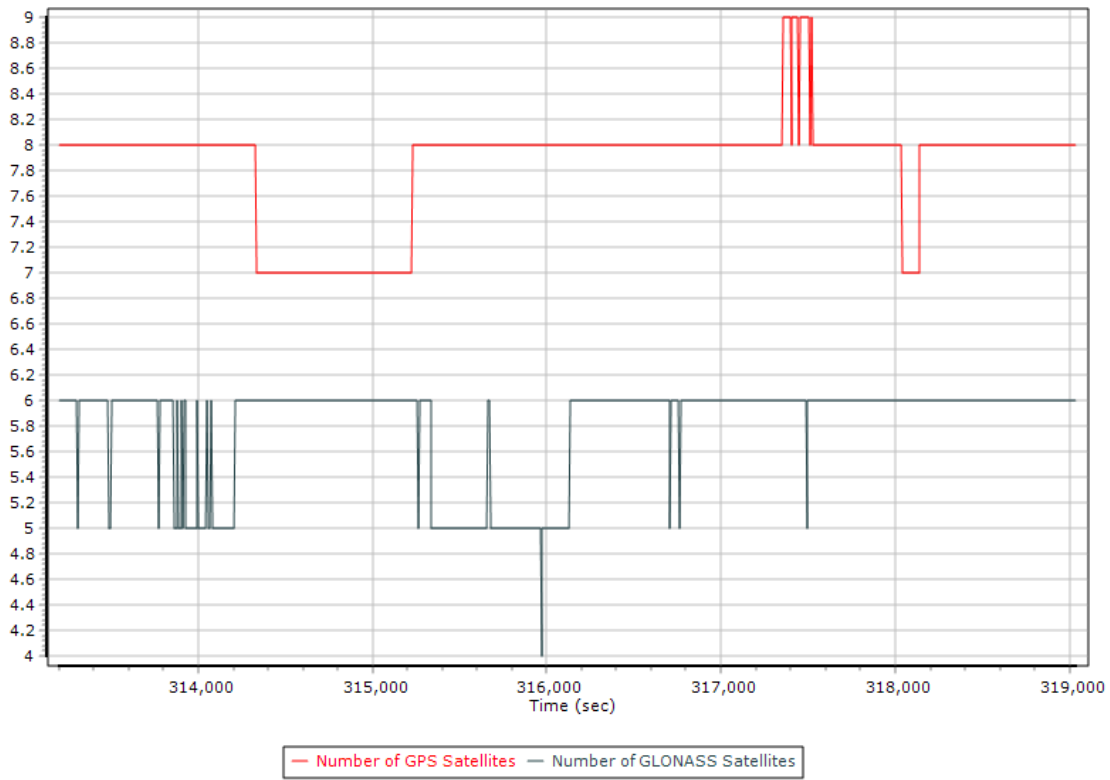


Reference to IMU Lever Arm		Reference to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 deg"/>
Reference to Primary GNSS Lever Arm		Aircraft to Reference 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			
	<3cm 10cm 50cm 1m 10m		

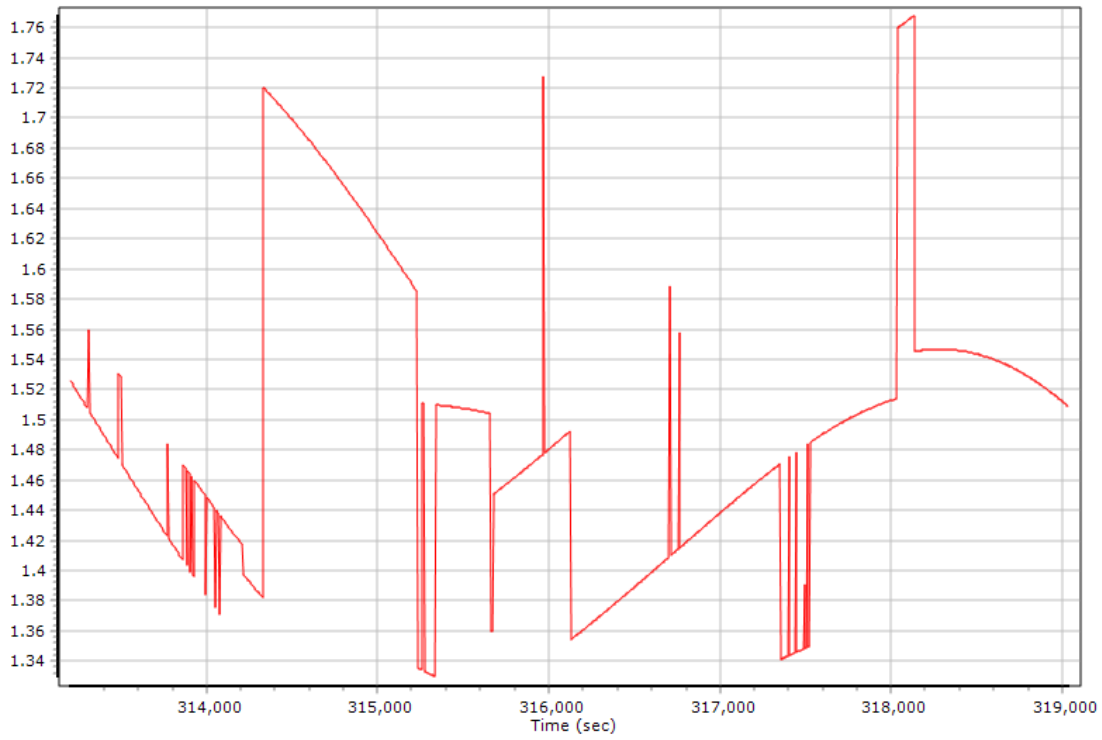
Timing			
Start	<input type="text" value="313182.000"/>	Data	Incr. (sec)
End	<input type="text" value="319045.000"/>	Output Record	0.005000
<input checked="" type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000
UTC Offset	<input type="text" value="18.000"/>		



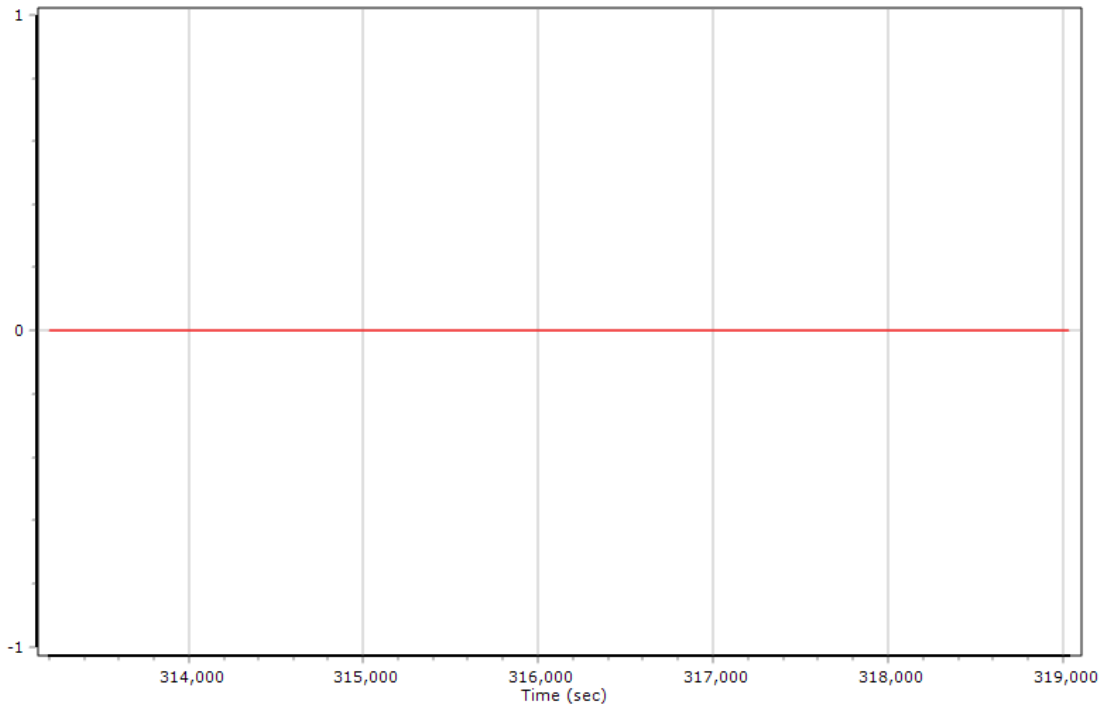




PDOP

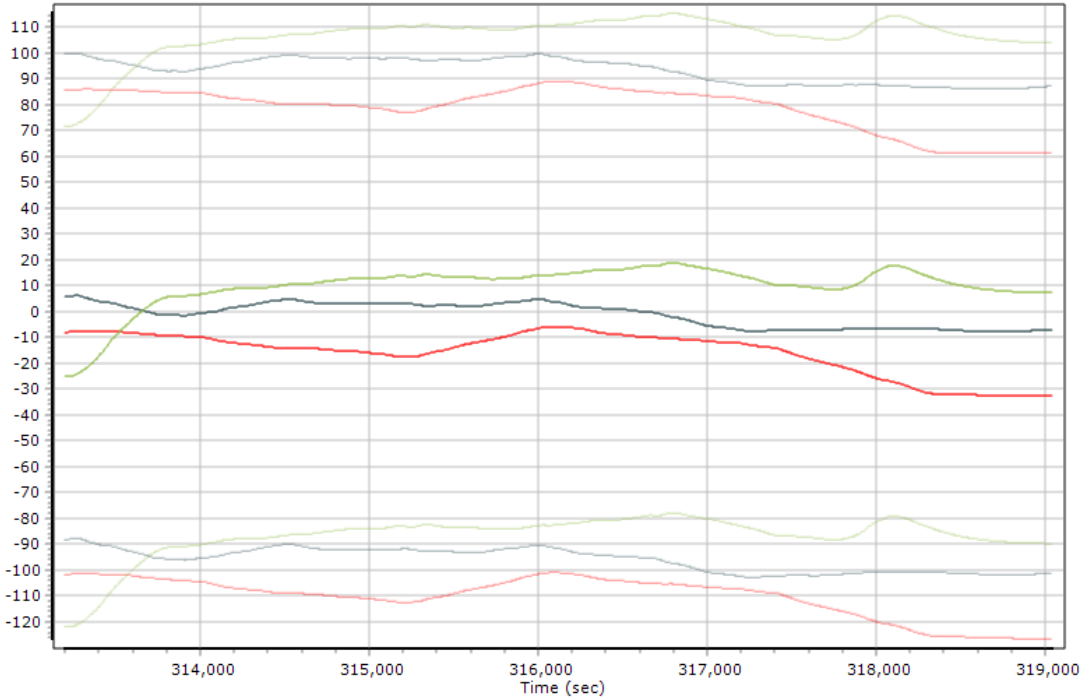


Processing mode

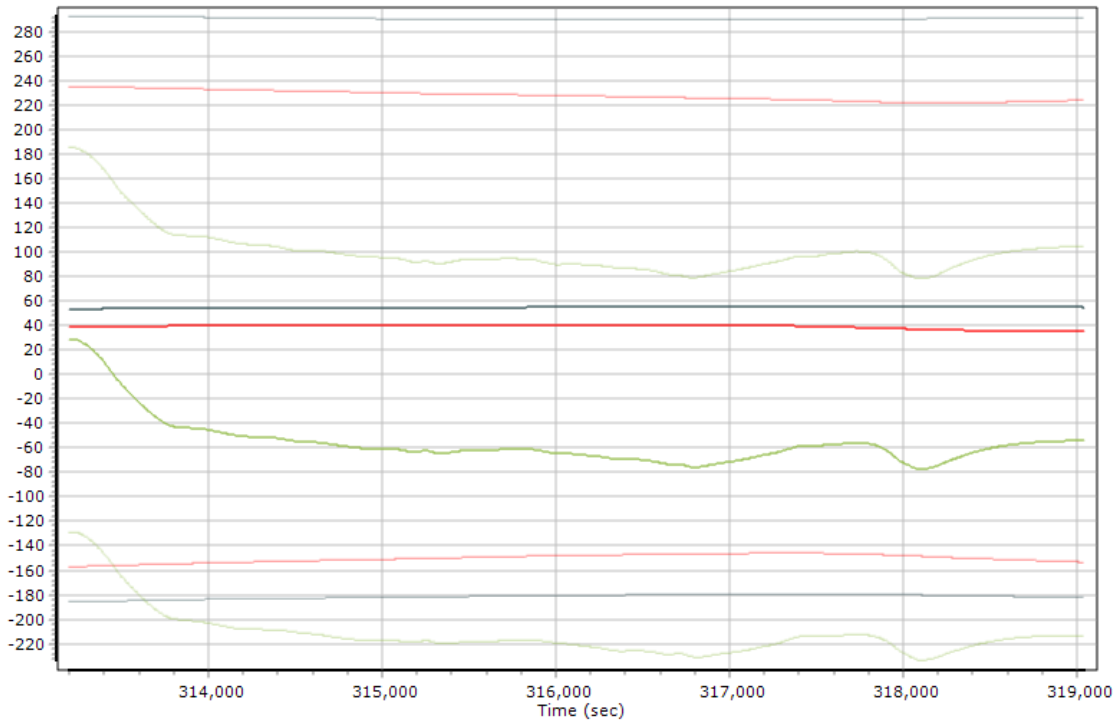


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

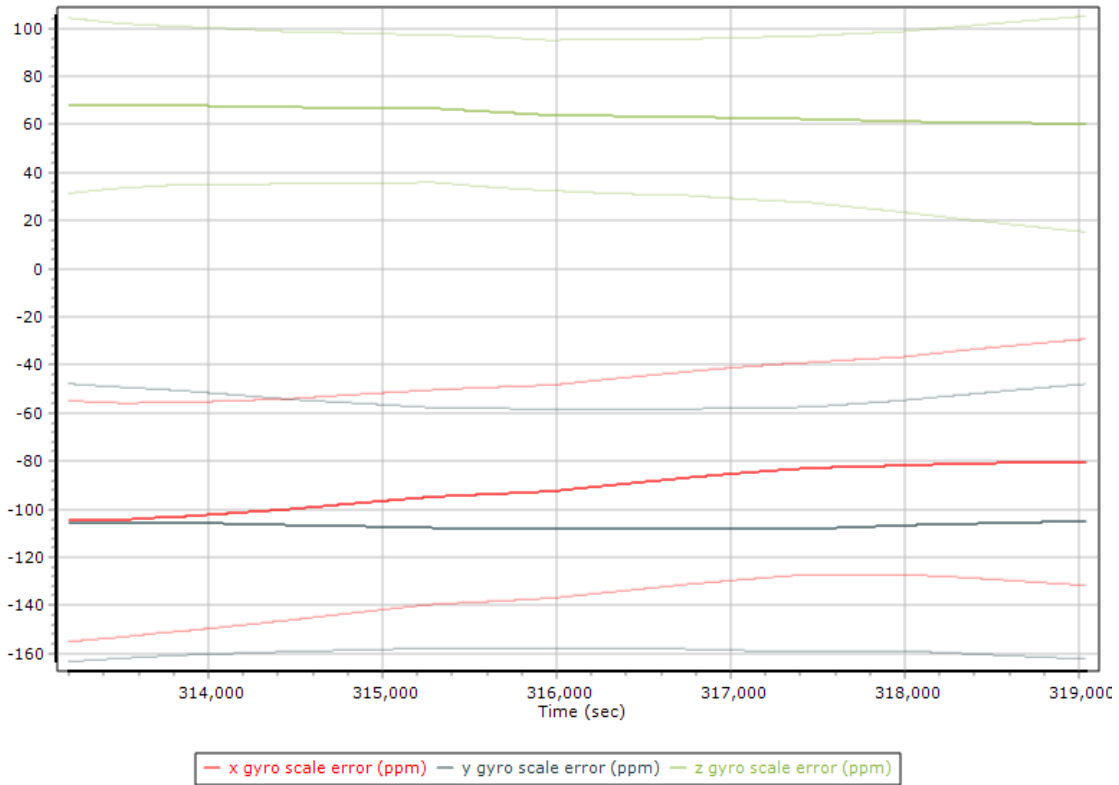
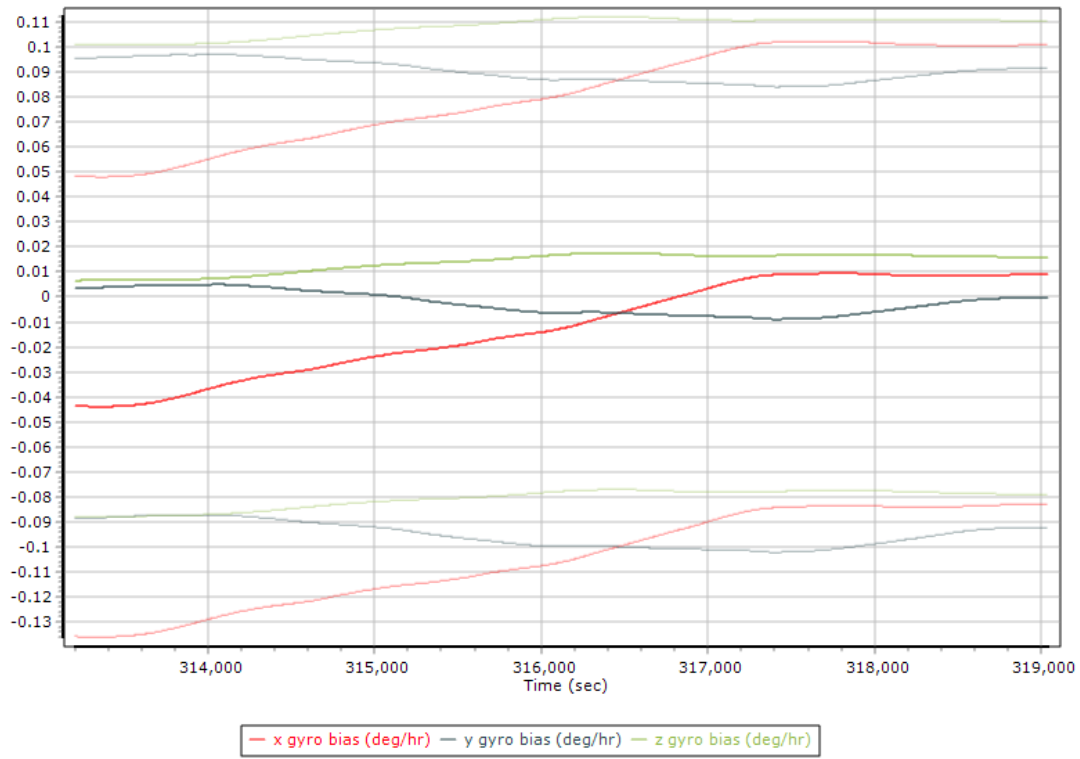
Sensor Errors



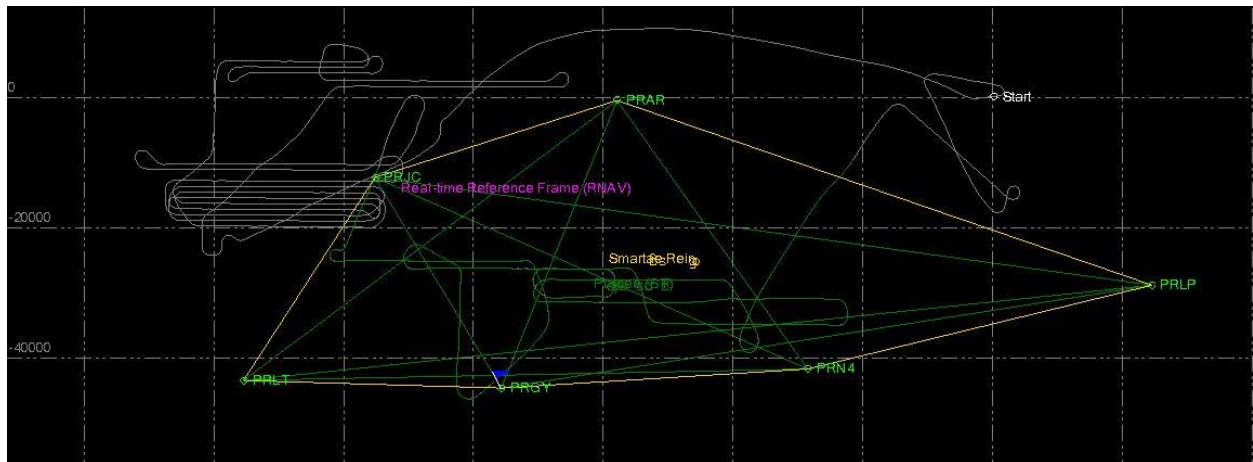
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



45A18280A



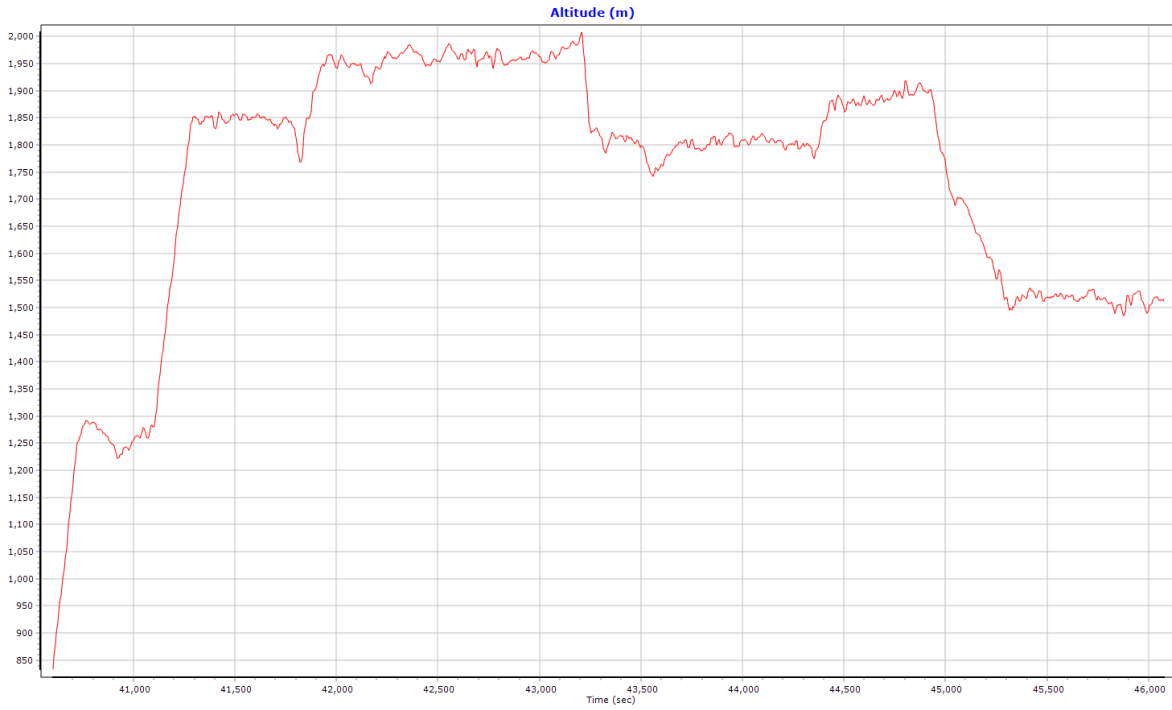
Stabilized Mount to IMU Lever Arm	Stabilized Mount to IMU Mounting Angles
X: -0.034 m	X: 0.000 deg
Y: -0.010 m	Y: 0.000 deg
Z: -0.352 m	Z: 0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	Aircraft to Stabilized Mount Mounting Angles
X: -0.049 m	X: 0.000 deg
Y: 0.003 m	Y: 0.000 deg
Z: -1.230 m	Z: 0.000 deg
Standard Deviation: <input type="range" value="0.03"/> <3cm 10cm 50cm 1m 10m	

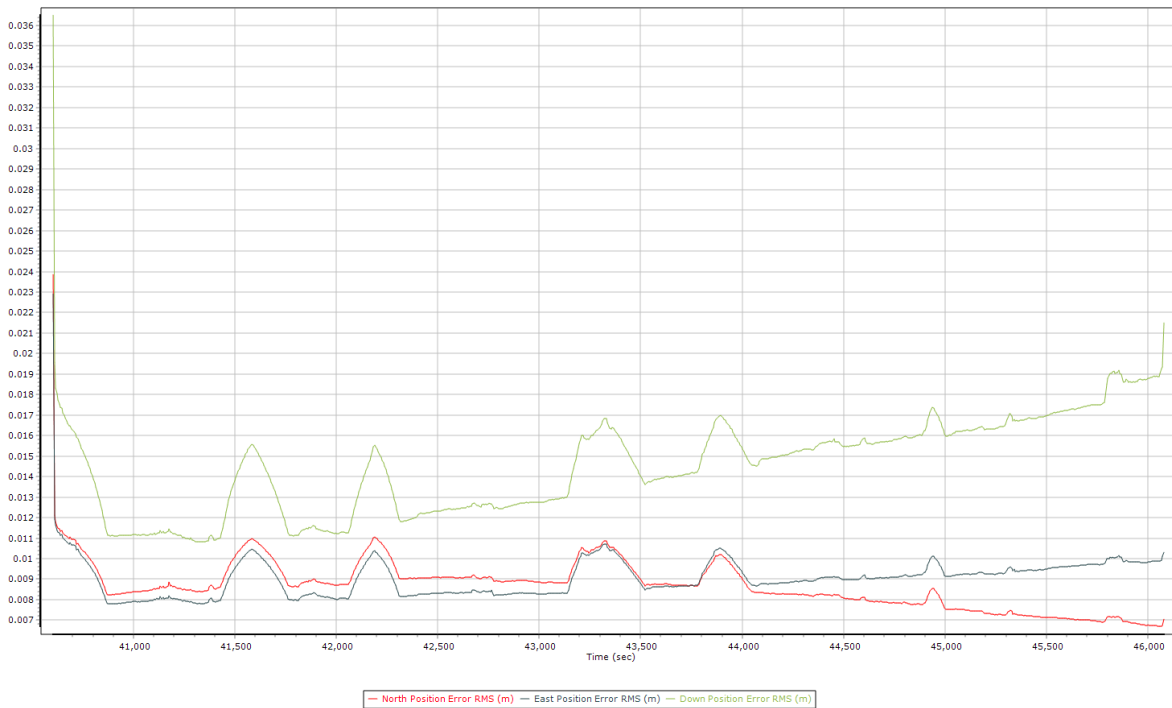
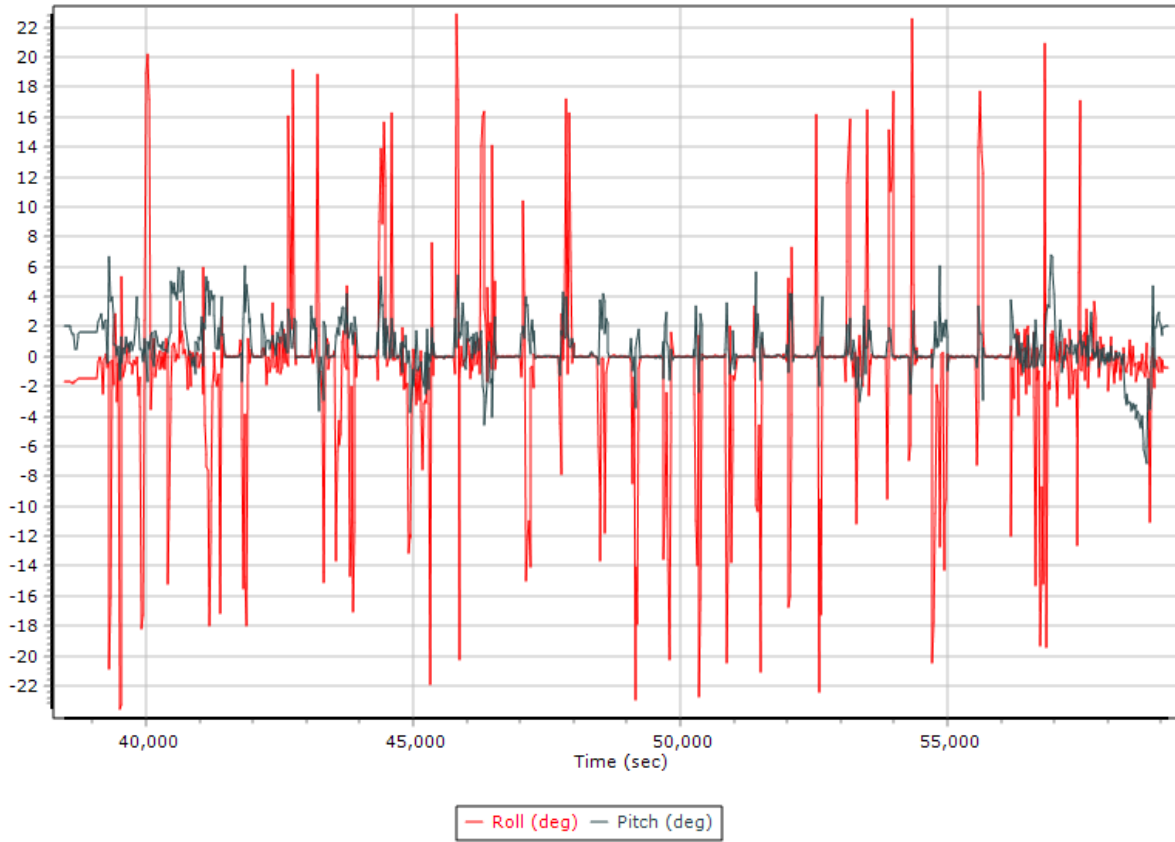
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

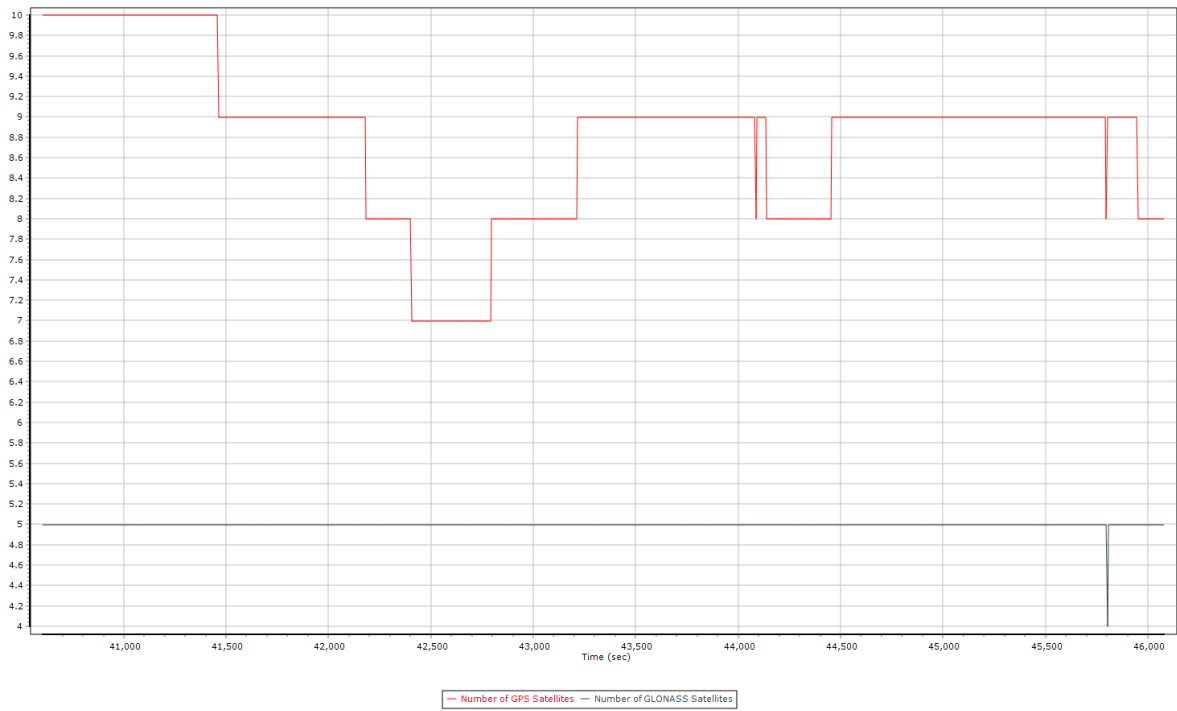
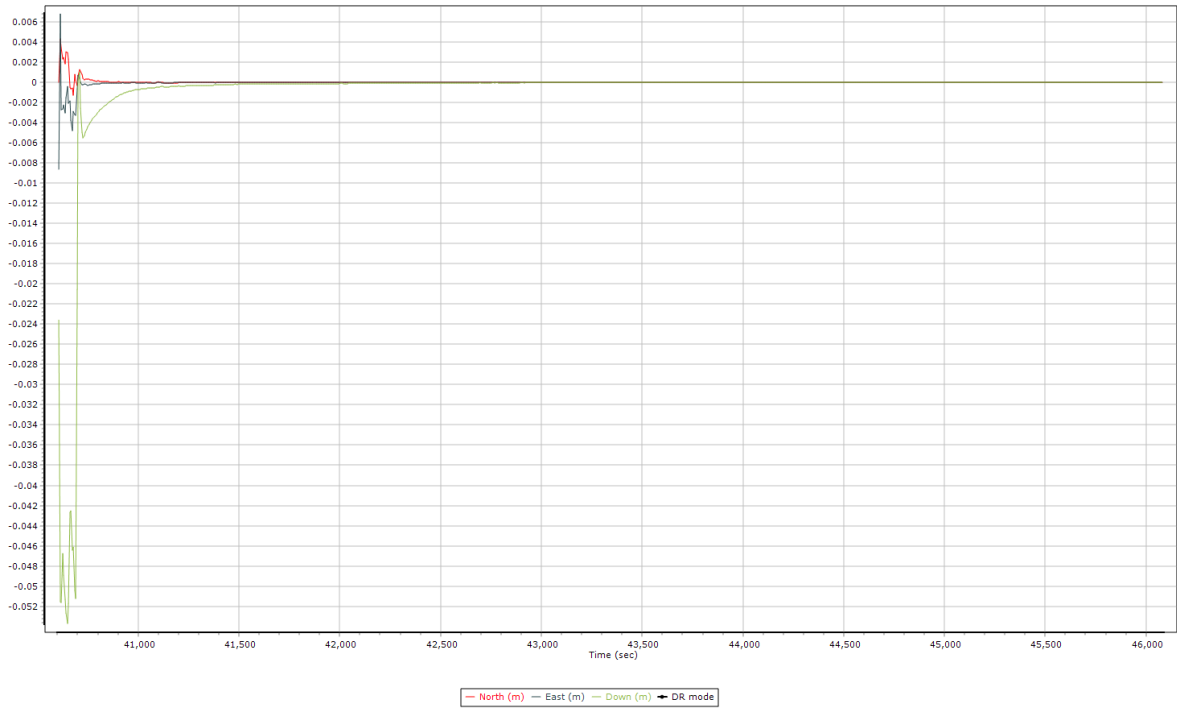
Timing

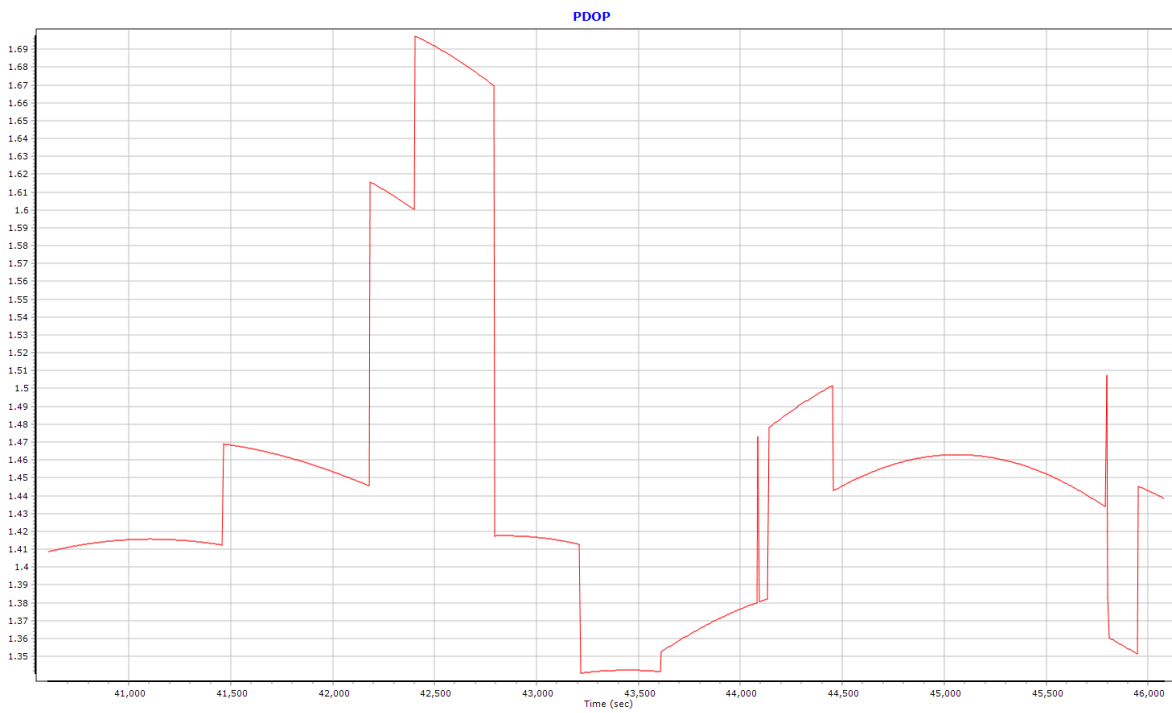
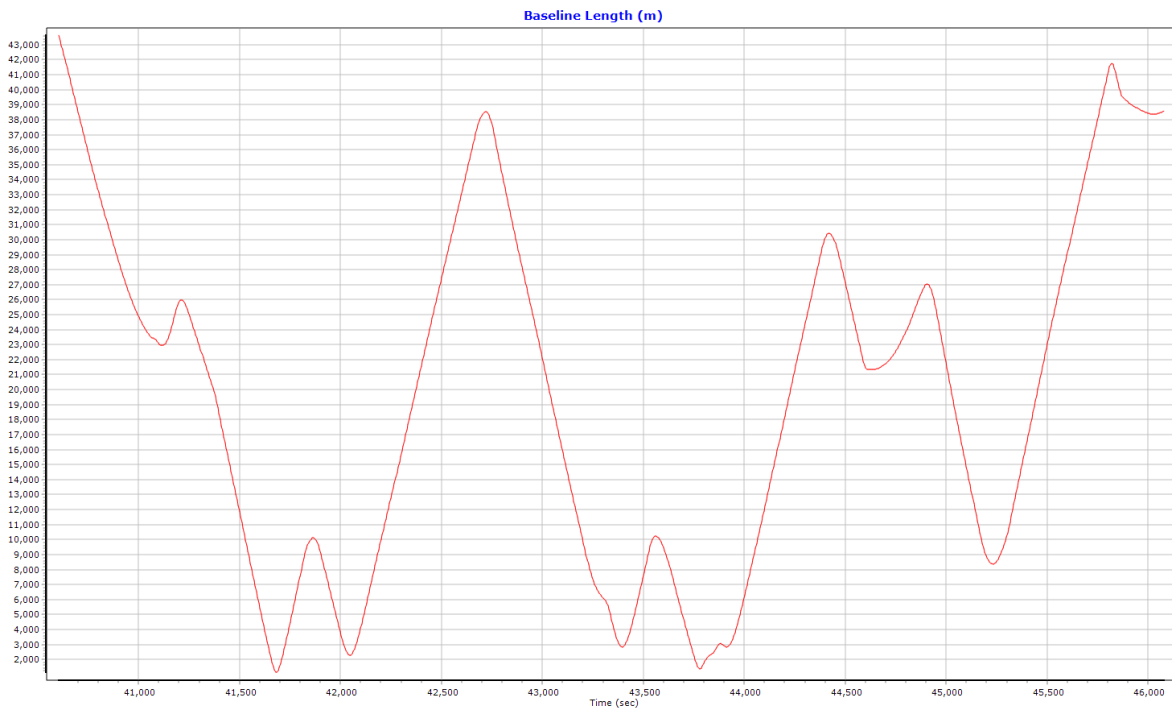
Start	40603.595	Data	Incr. (sec)
End	46084.647	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

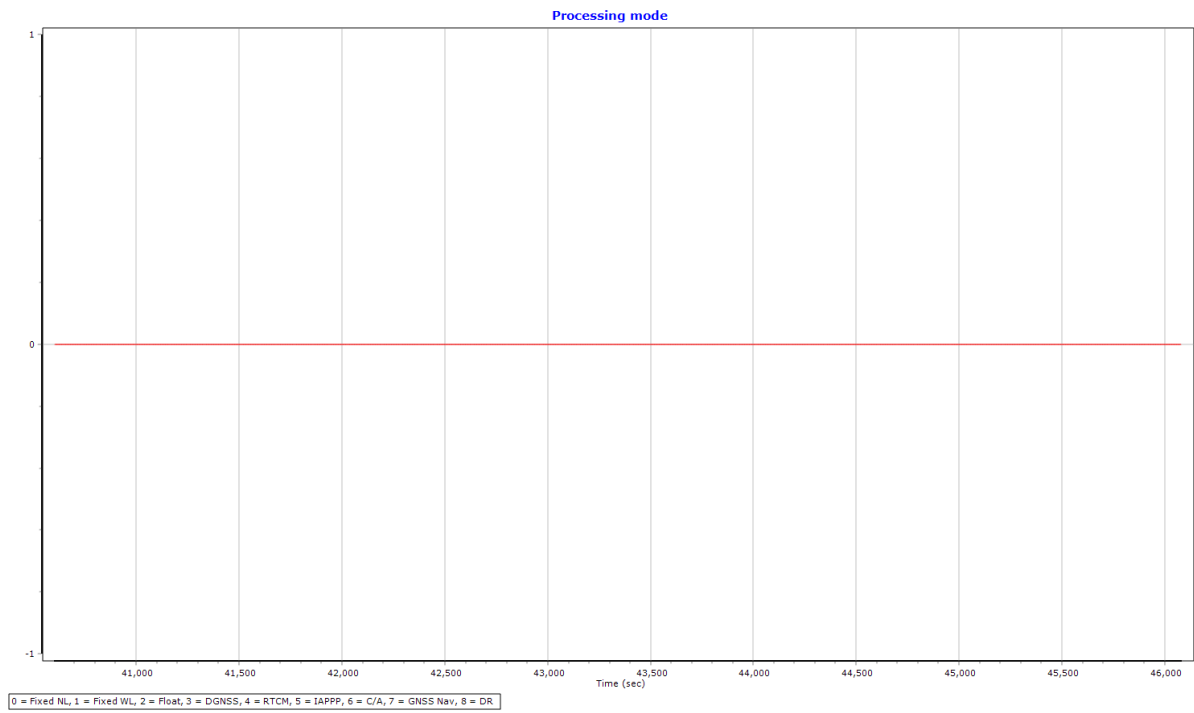
UTC Offset



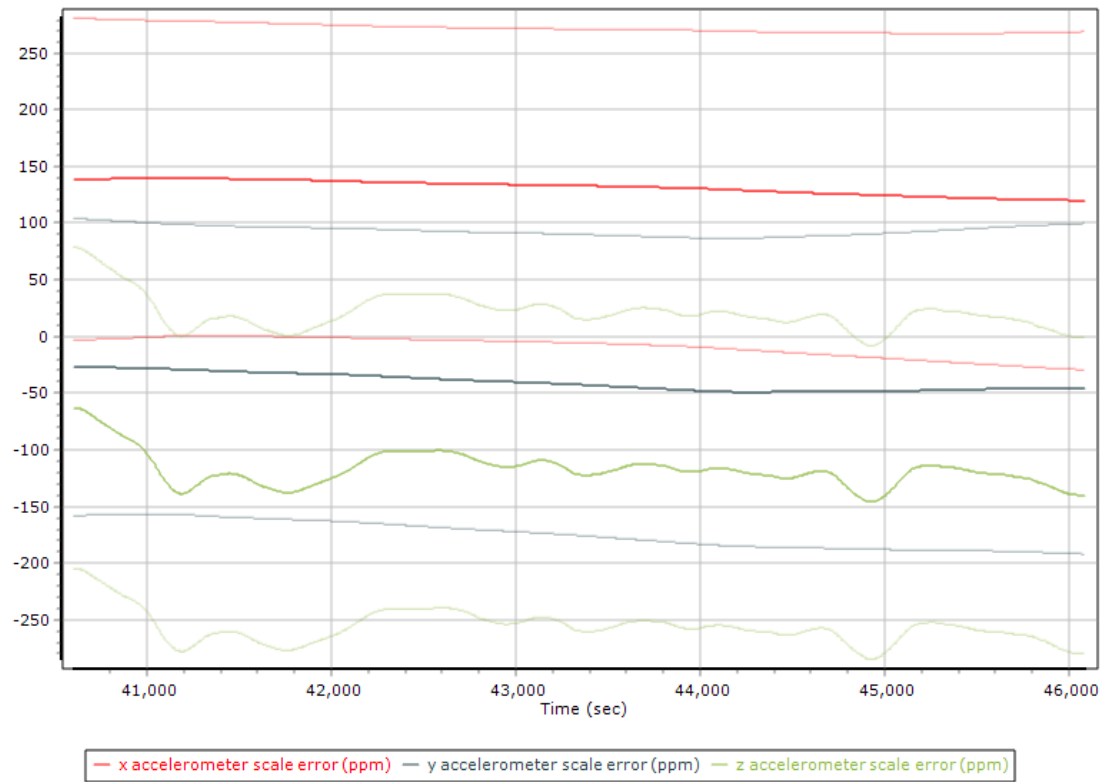
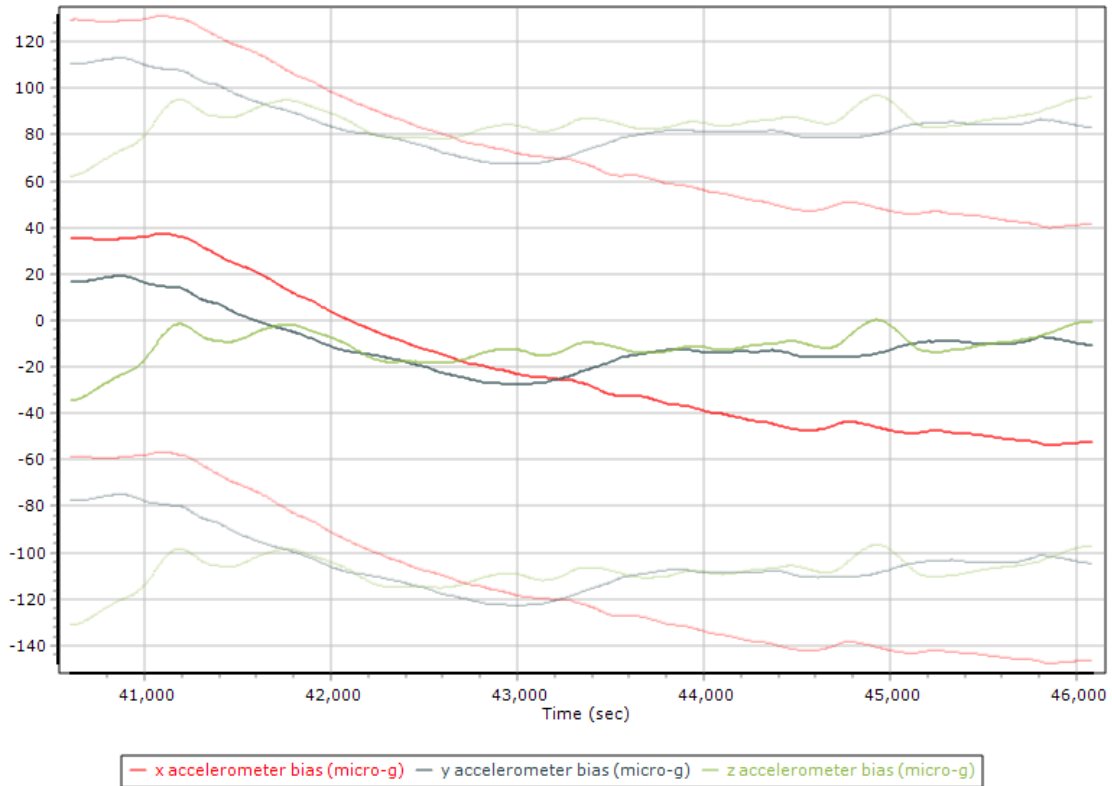


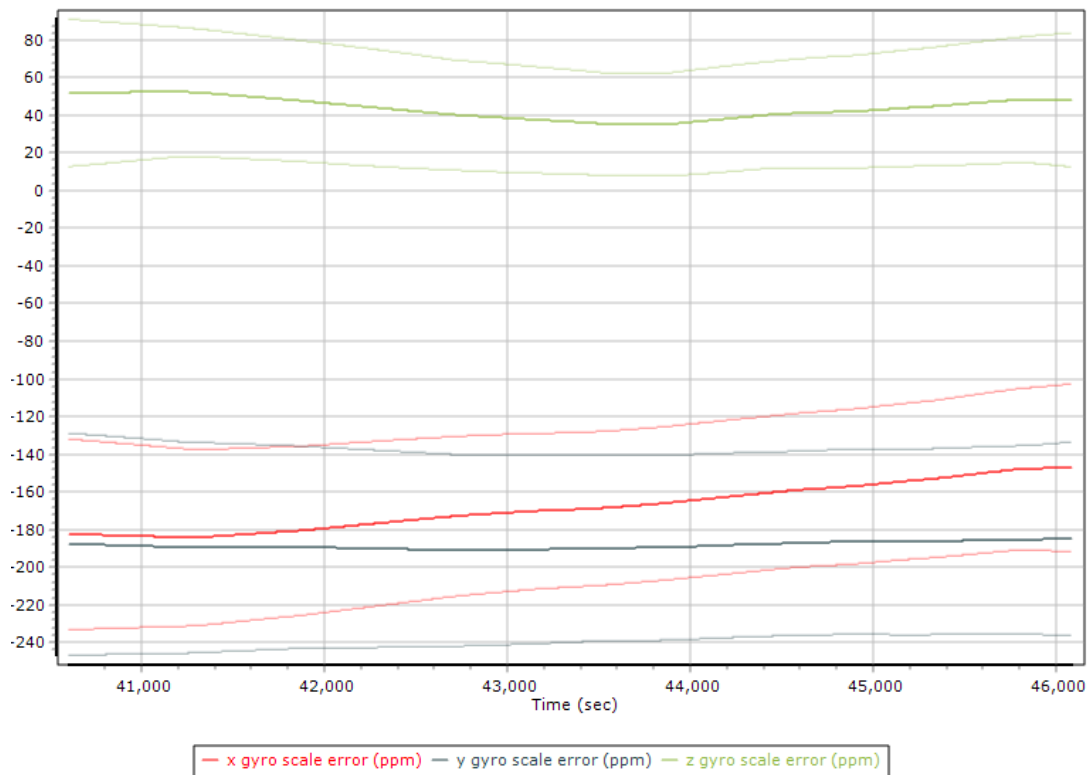
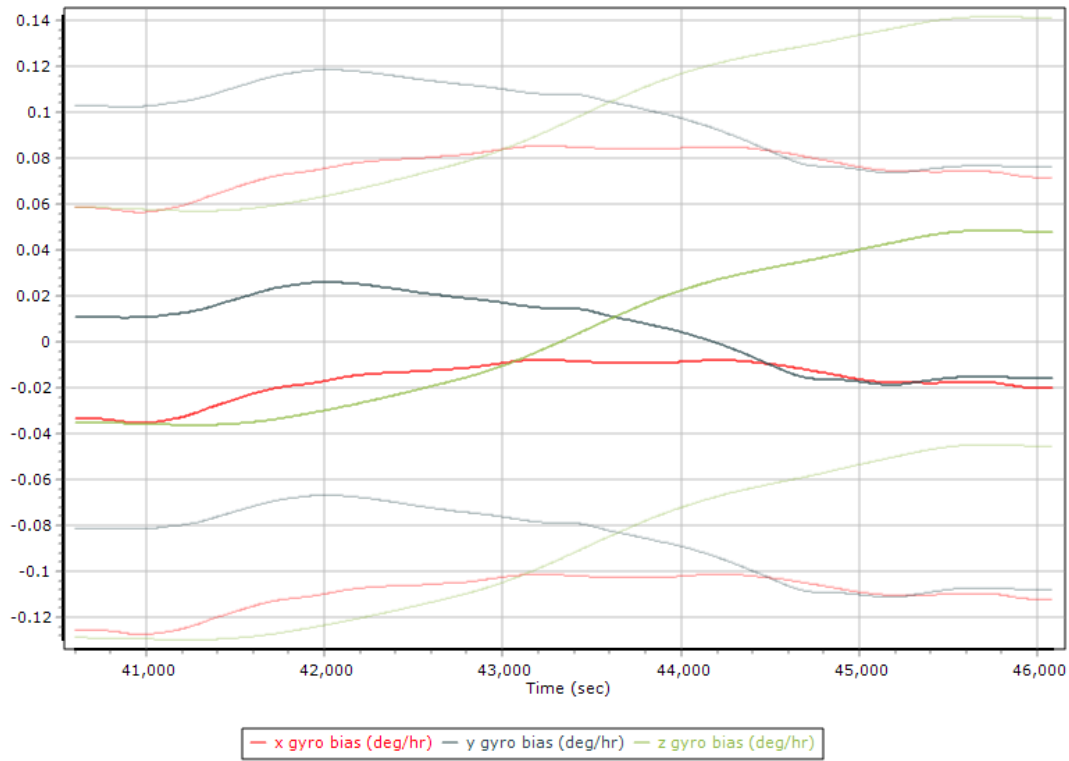




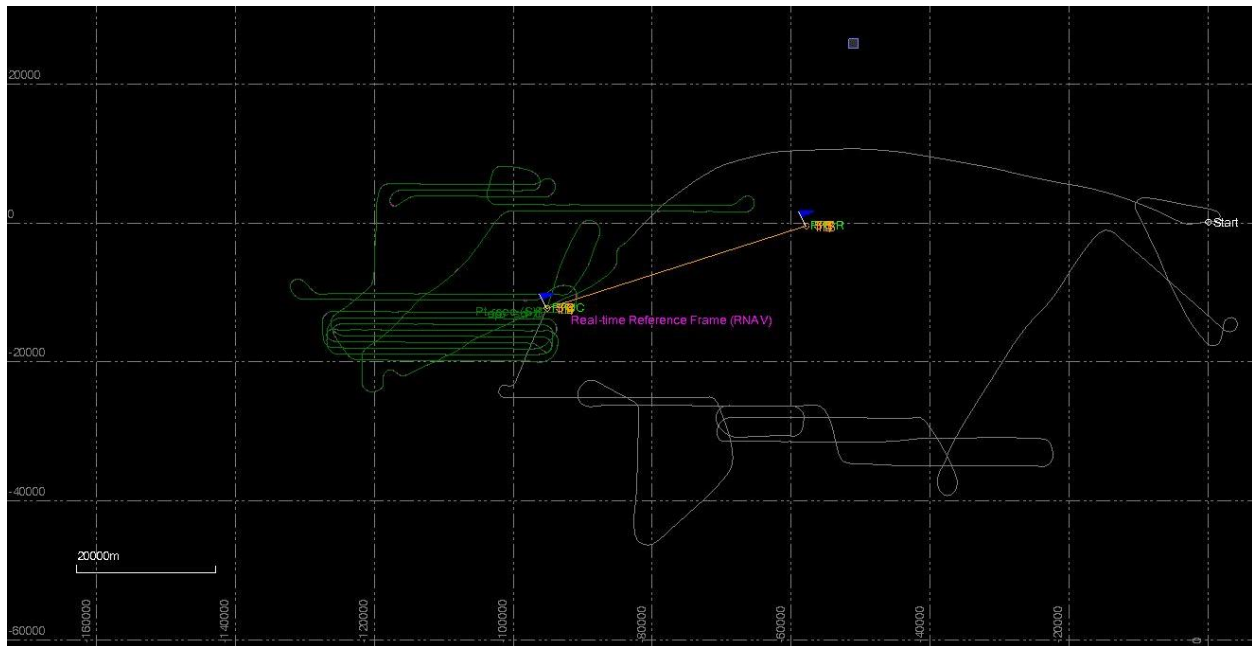


Sensor Errors





45A18280A2



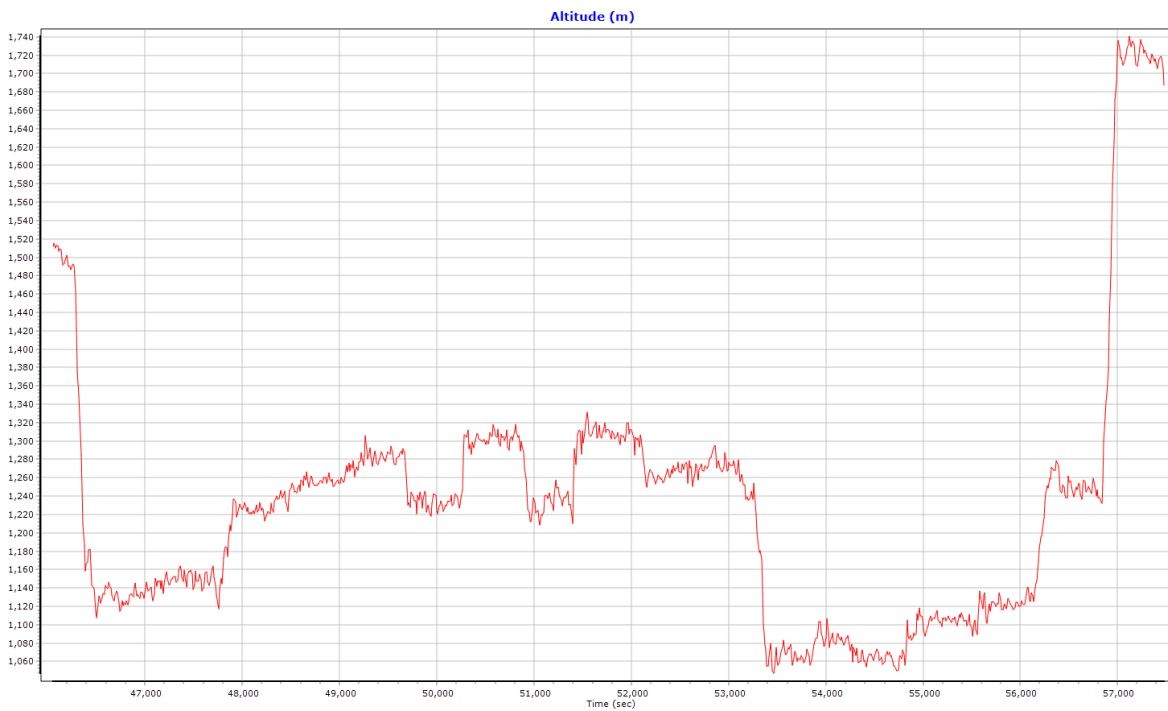
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	-0.034 m	X	0.000 deg
Y	-0.010 m	Y	0.000 deg
Z	-0.352 m	Z	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm		Aircraft to Stabilized Mount Mounting Angles	
X	-0.049 m	X	0.000 deg
Y	0.003 m	Y	0.000 deg
Z	-1.230 m	Z	0.000 deg
Standard Deviation			

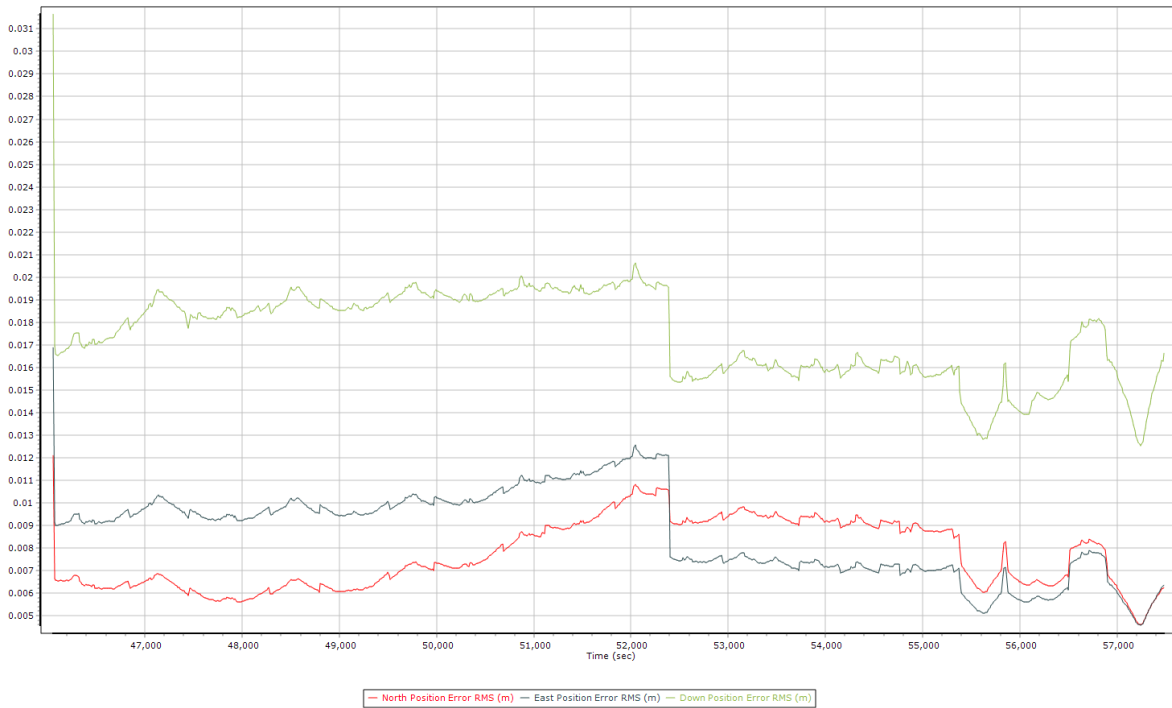
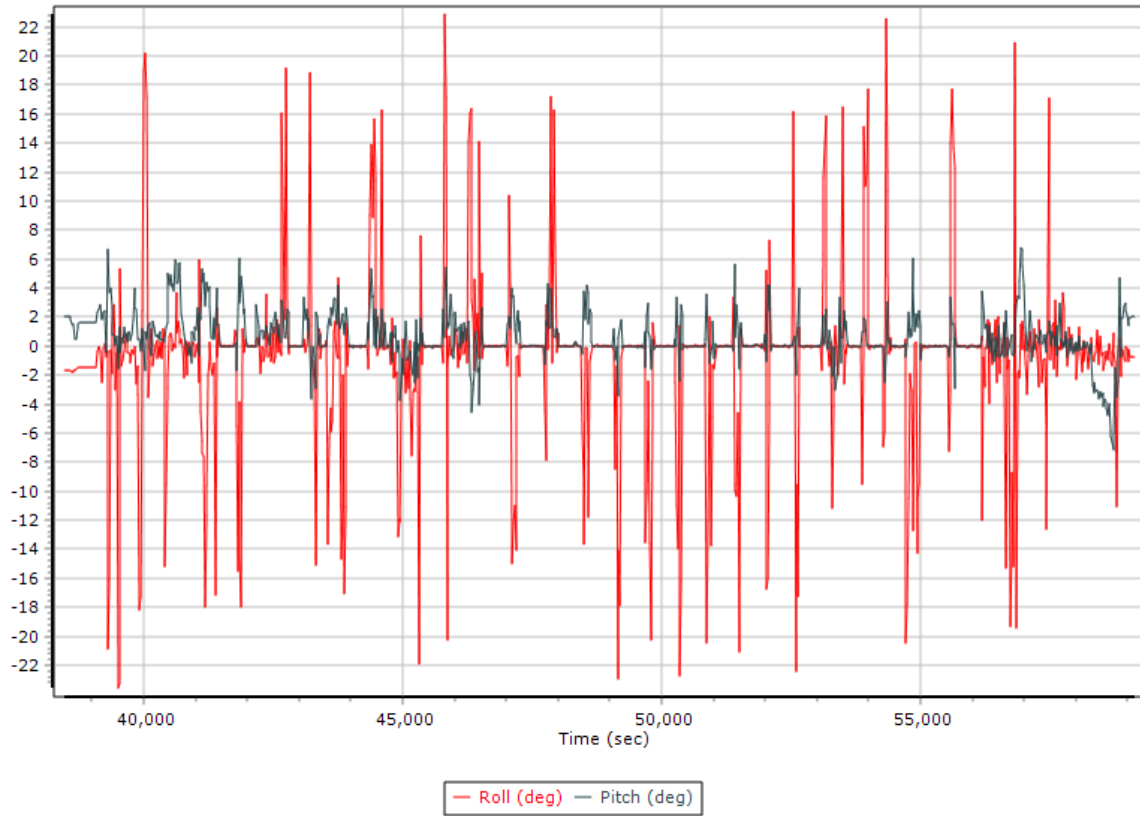
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

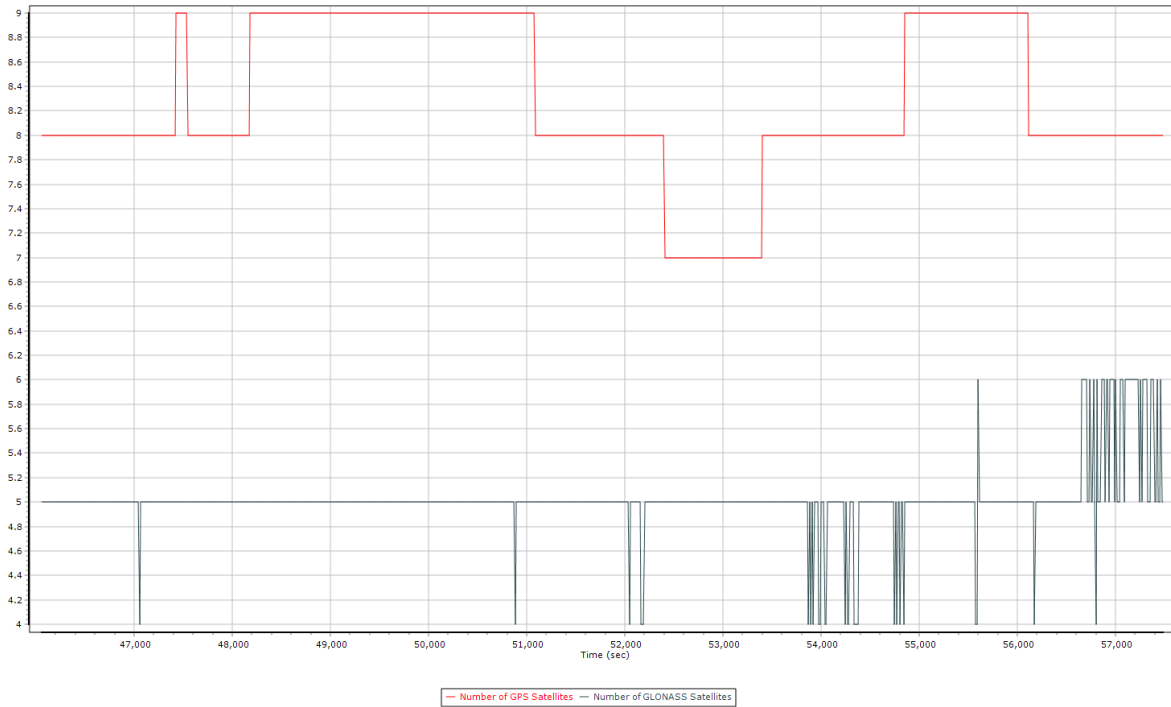
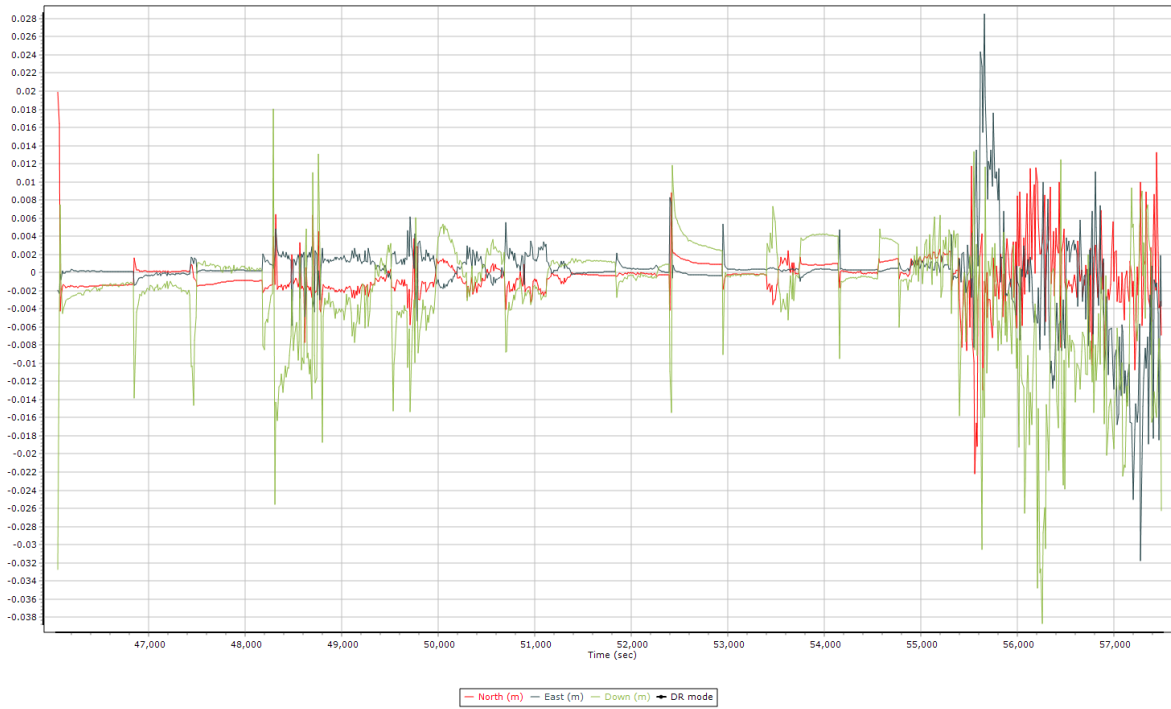
Timing

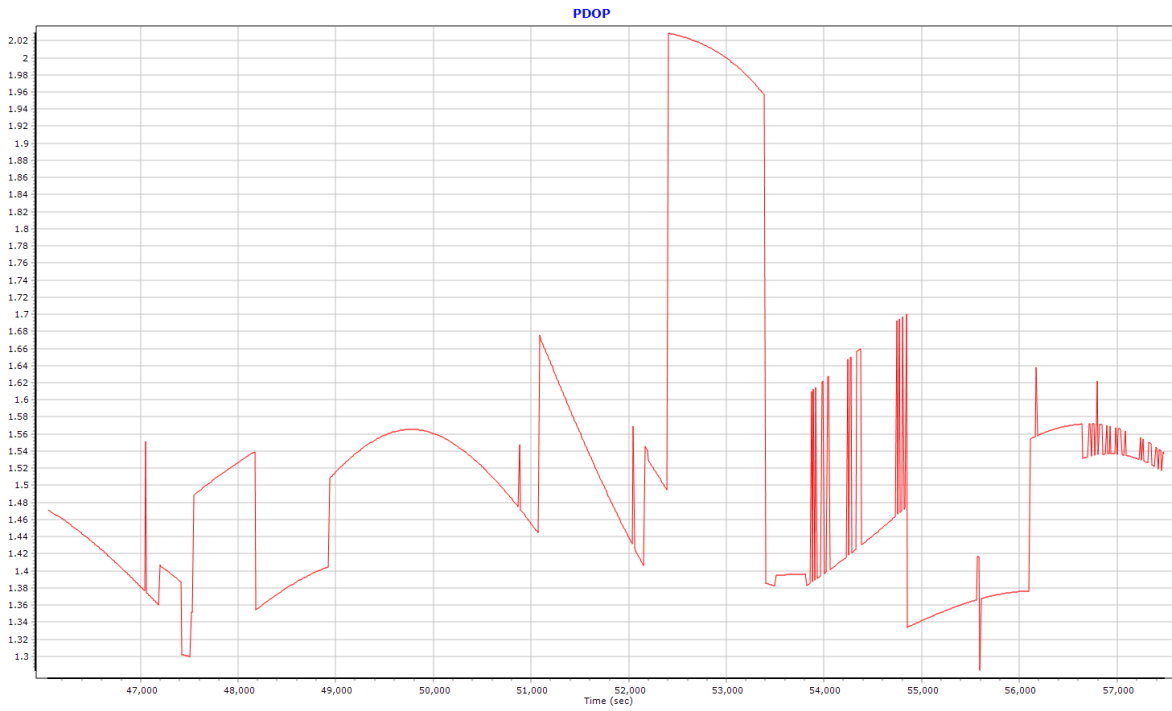
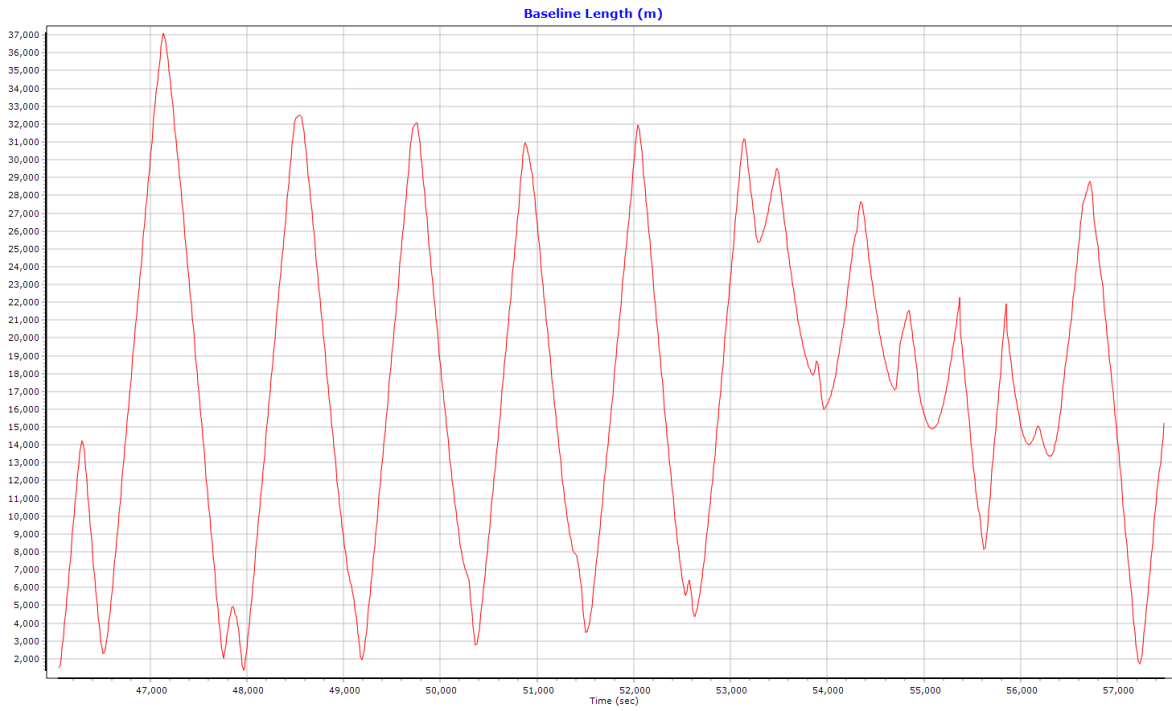
Start	46054.641	Data	Incr. (sec)
End	57496.858	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset: 18.000



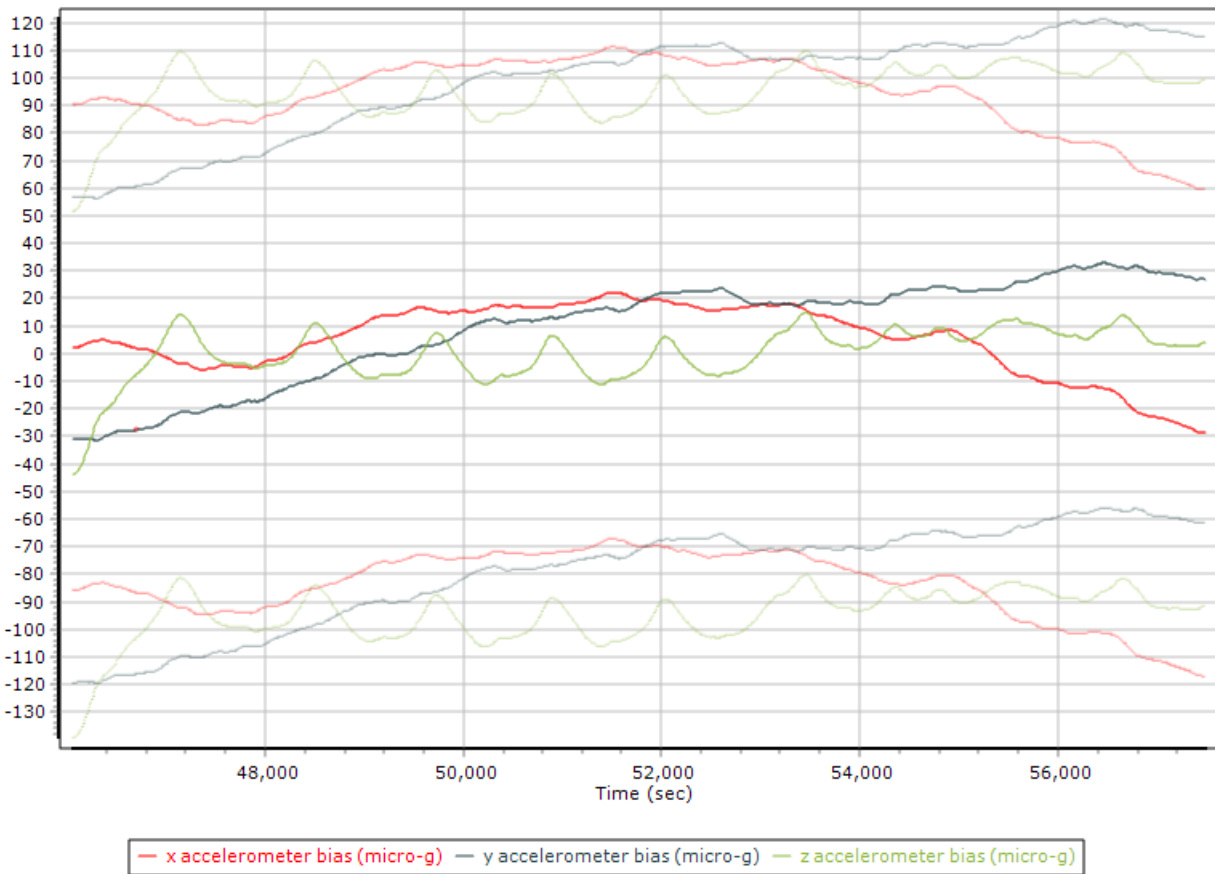


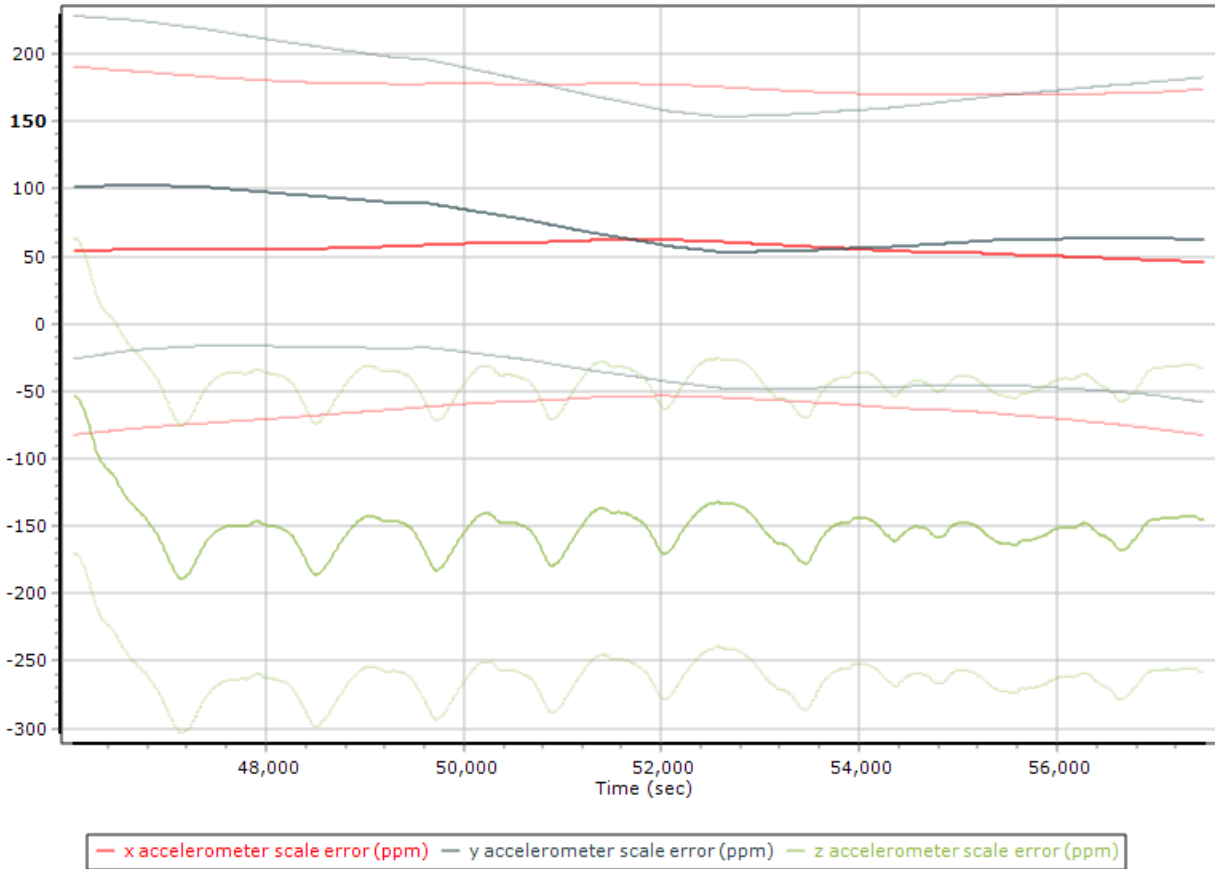


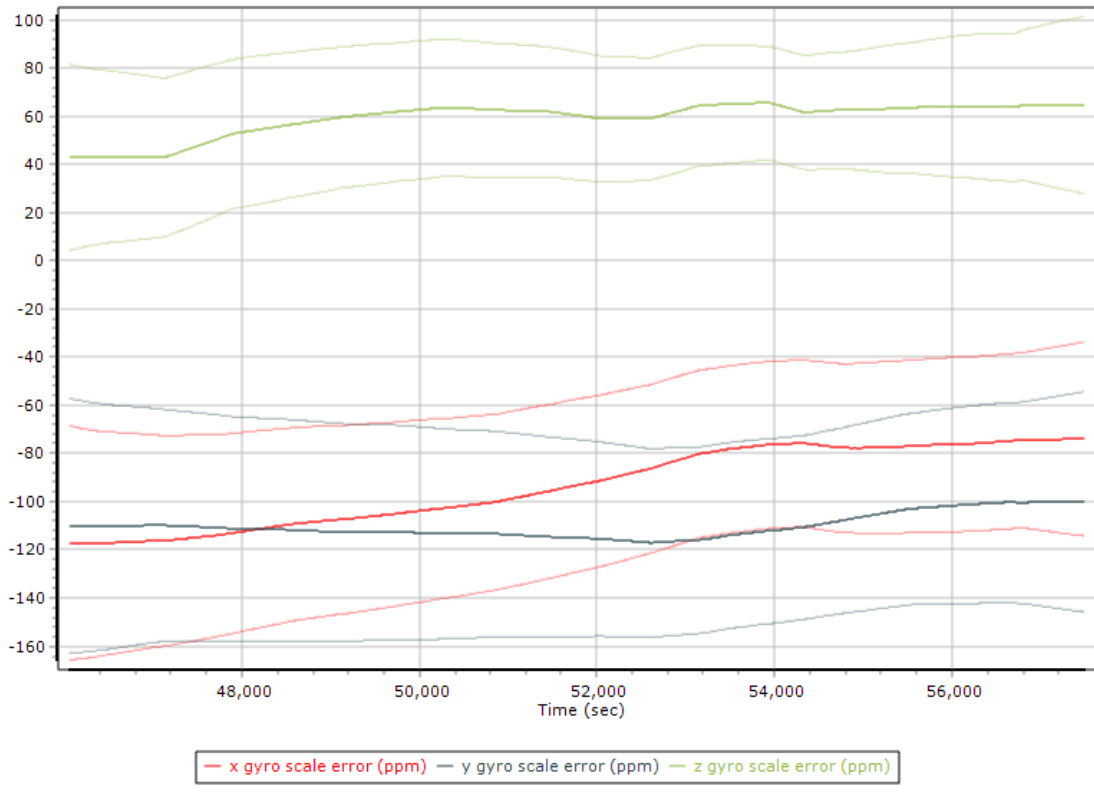
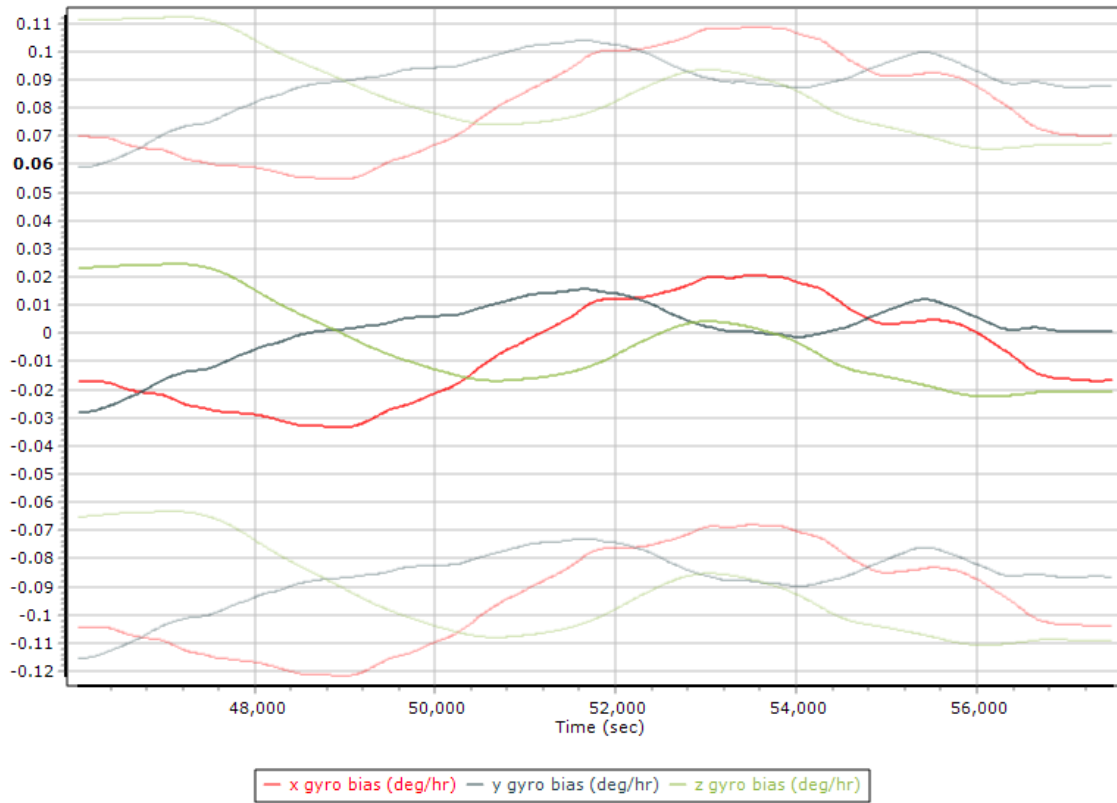




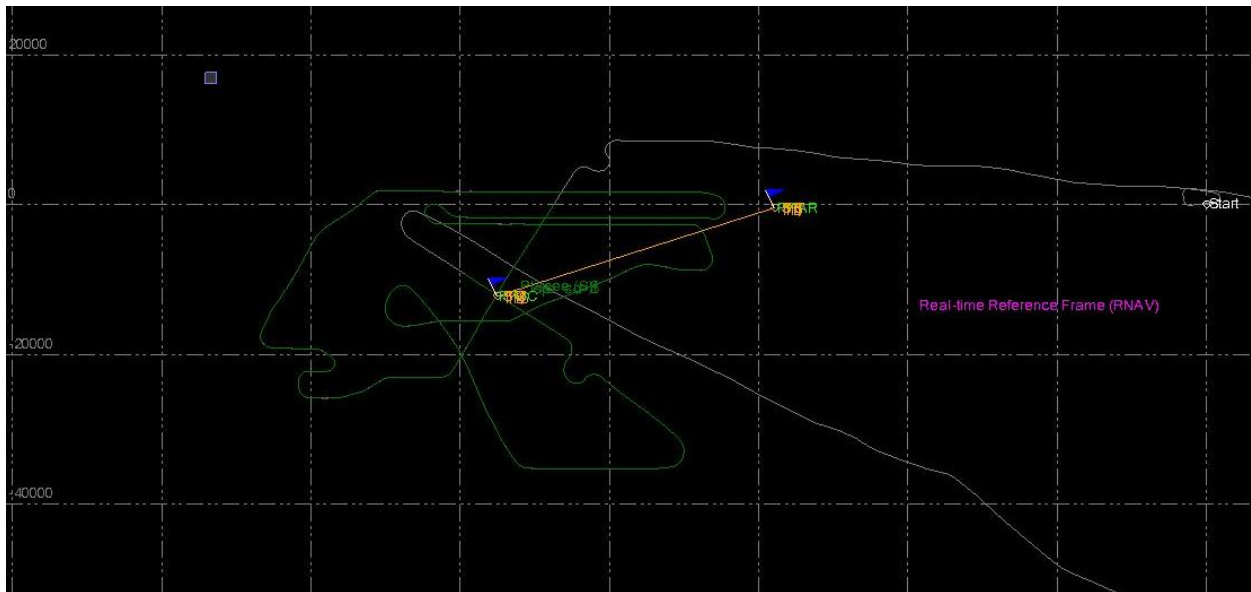
Sensor Errors







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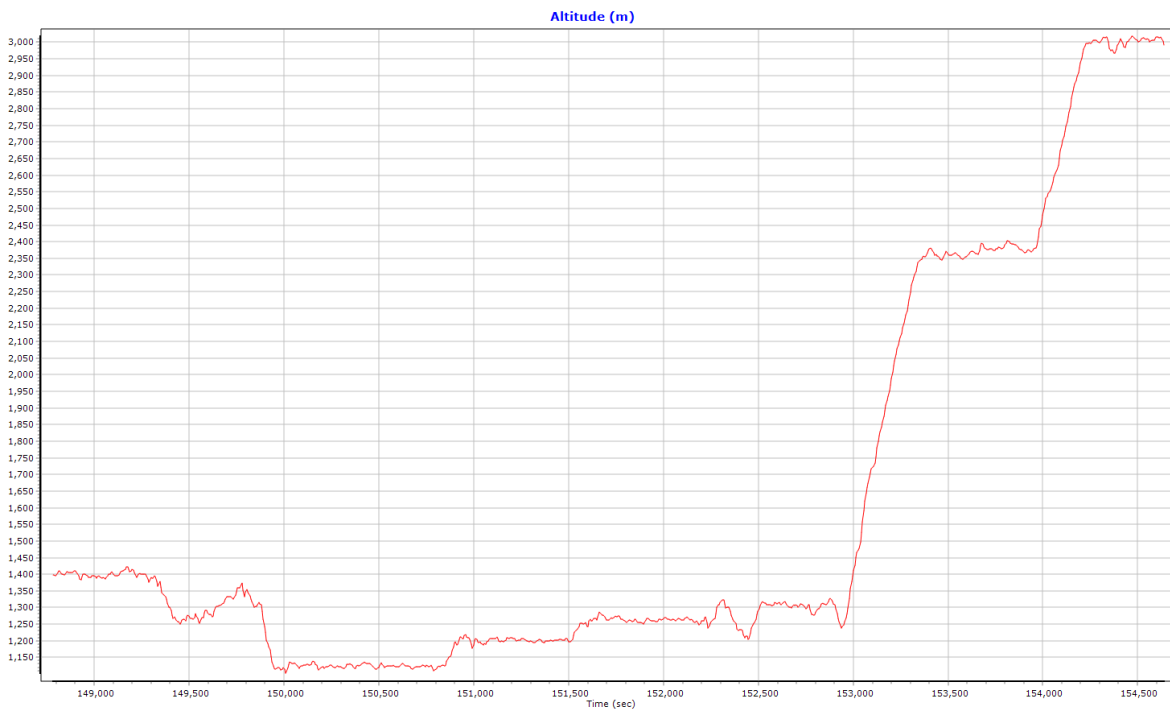
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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		

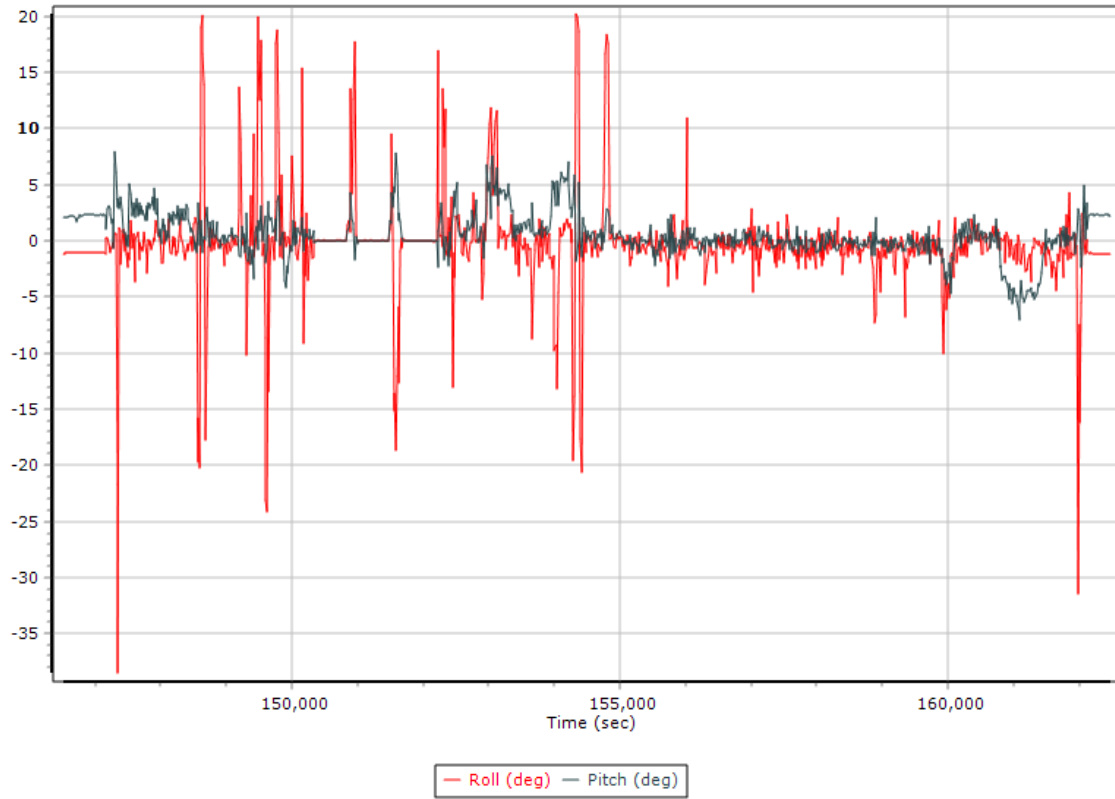
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

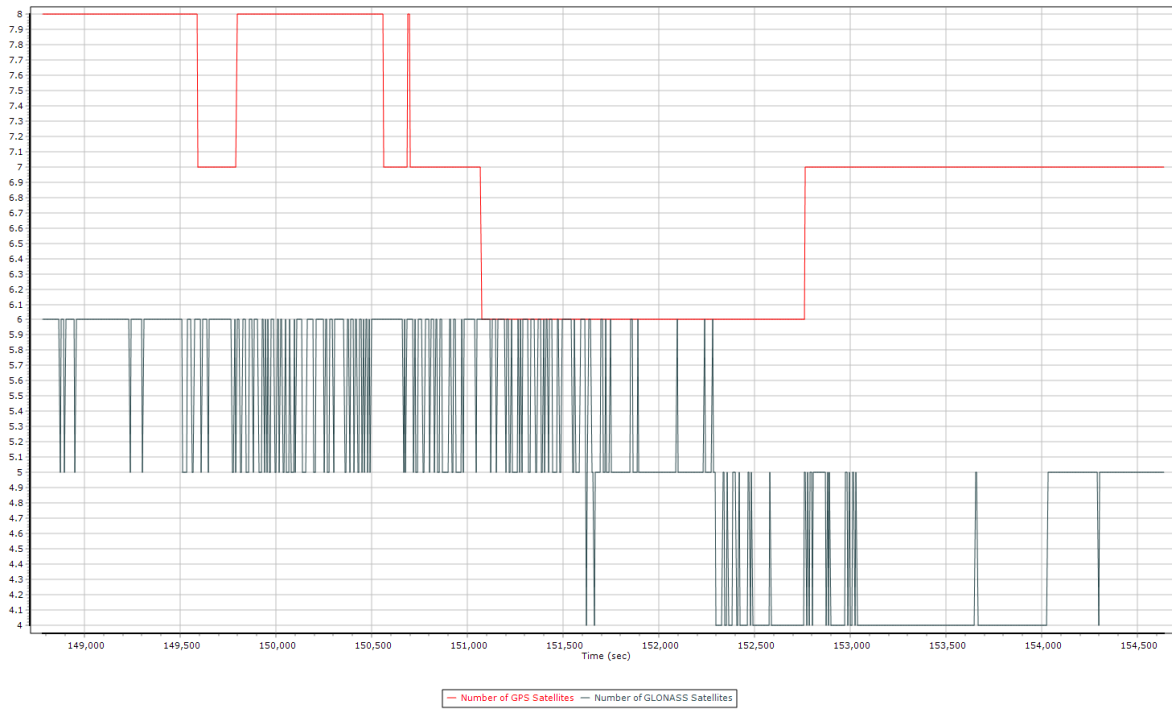
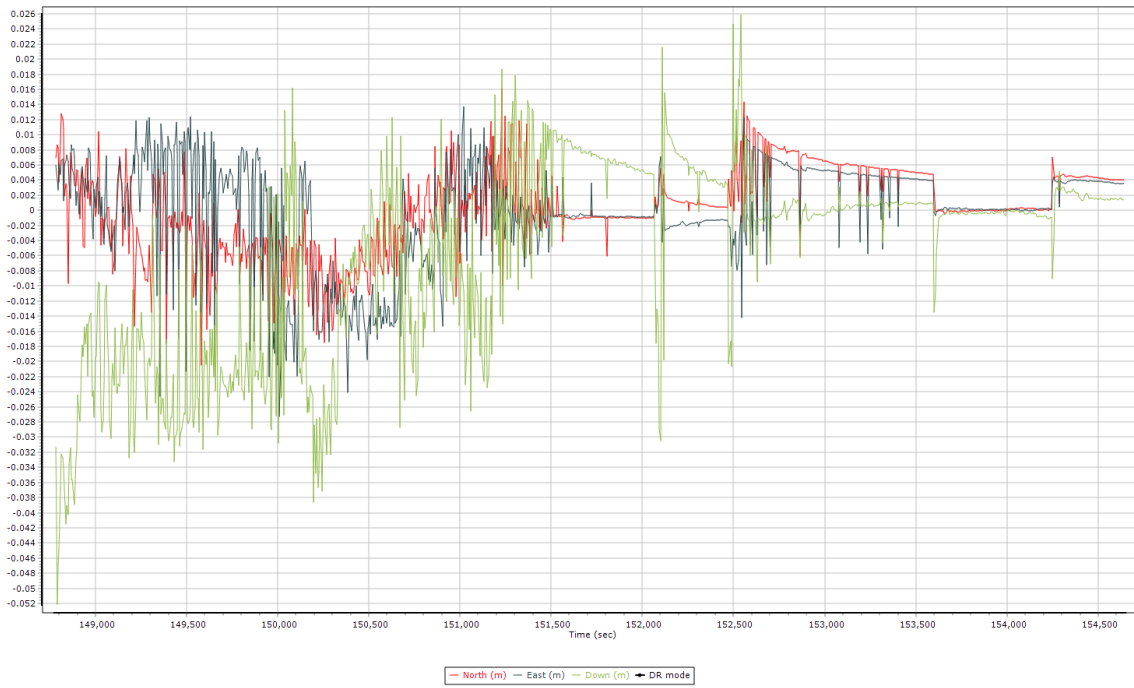
Timing

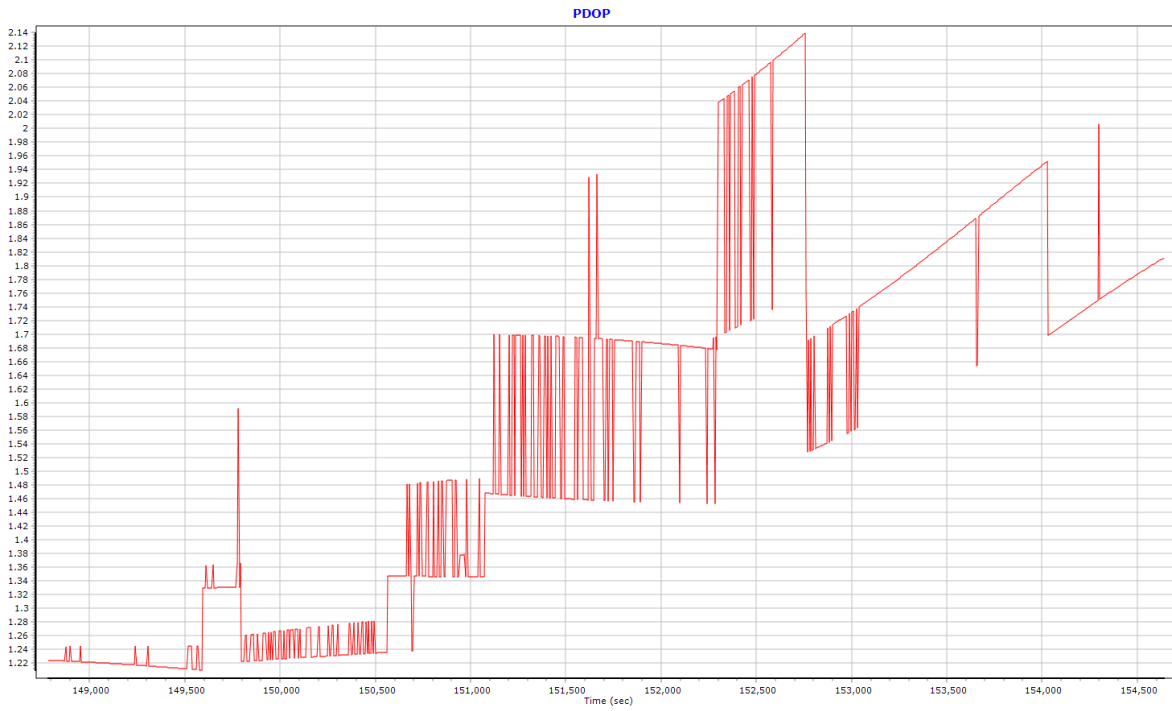
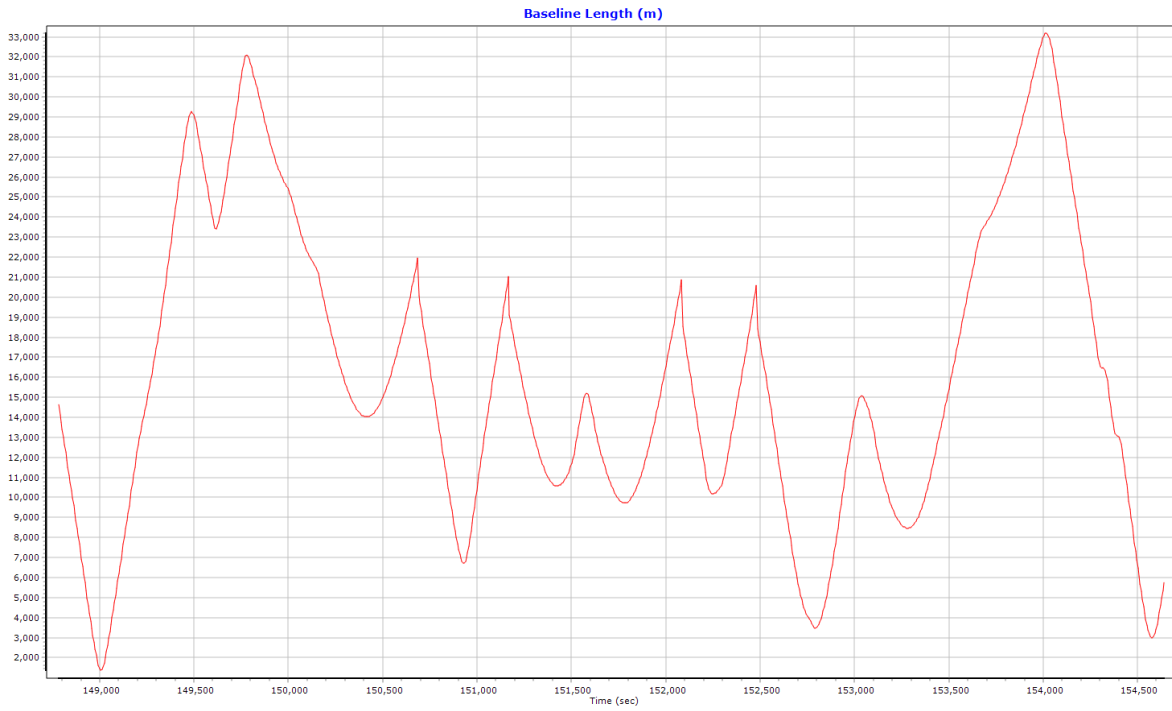
Start	148780.893	Data	Incr. (sec)
End	154645.030	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset: 18.000



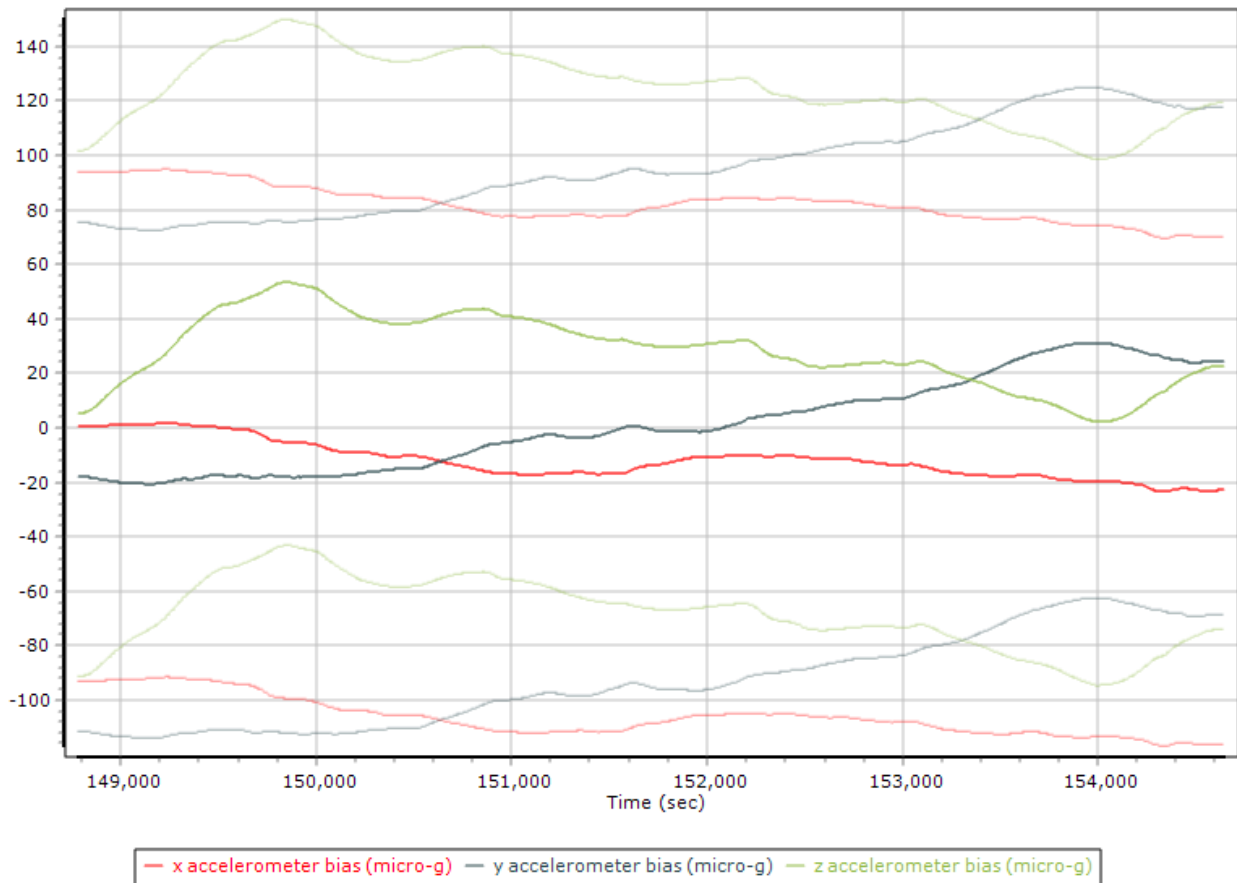


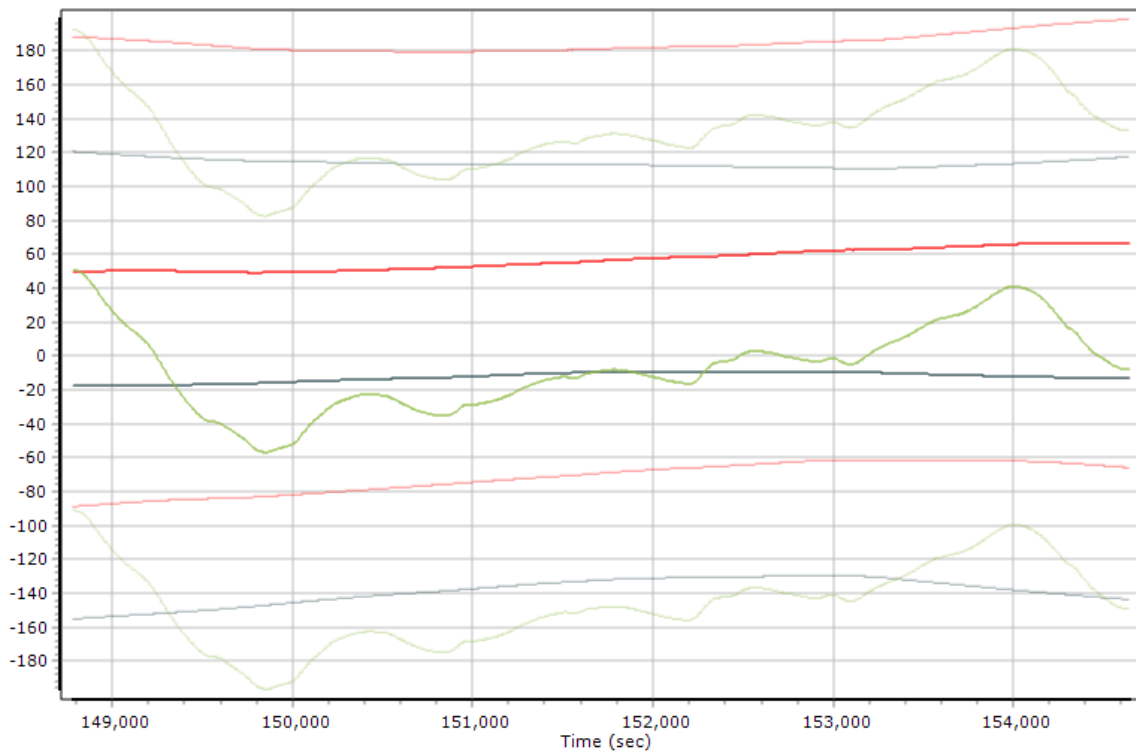




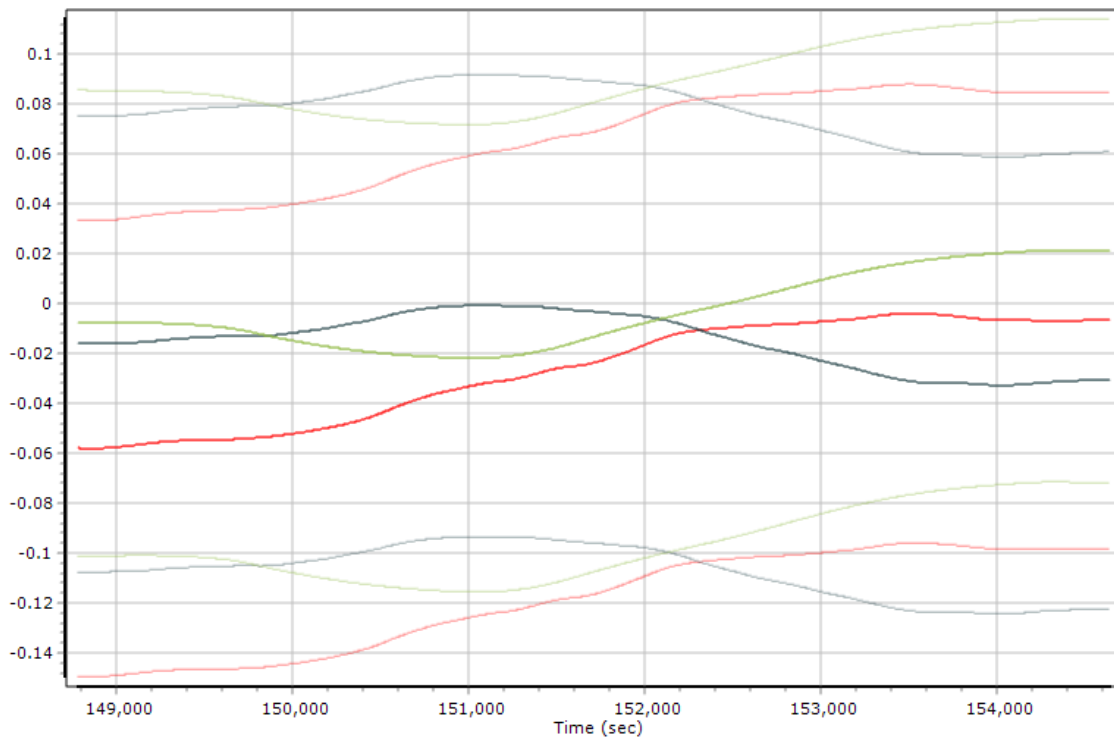


Sensor Errors

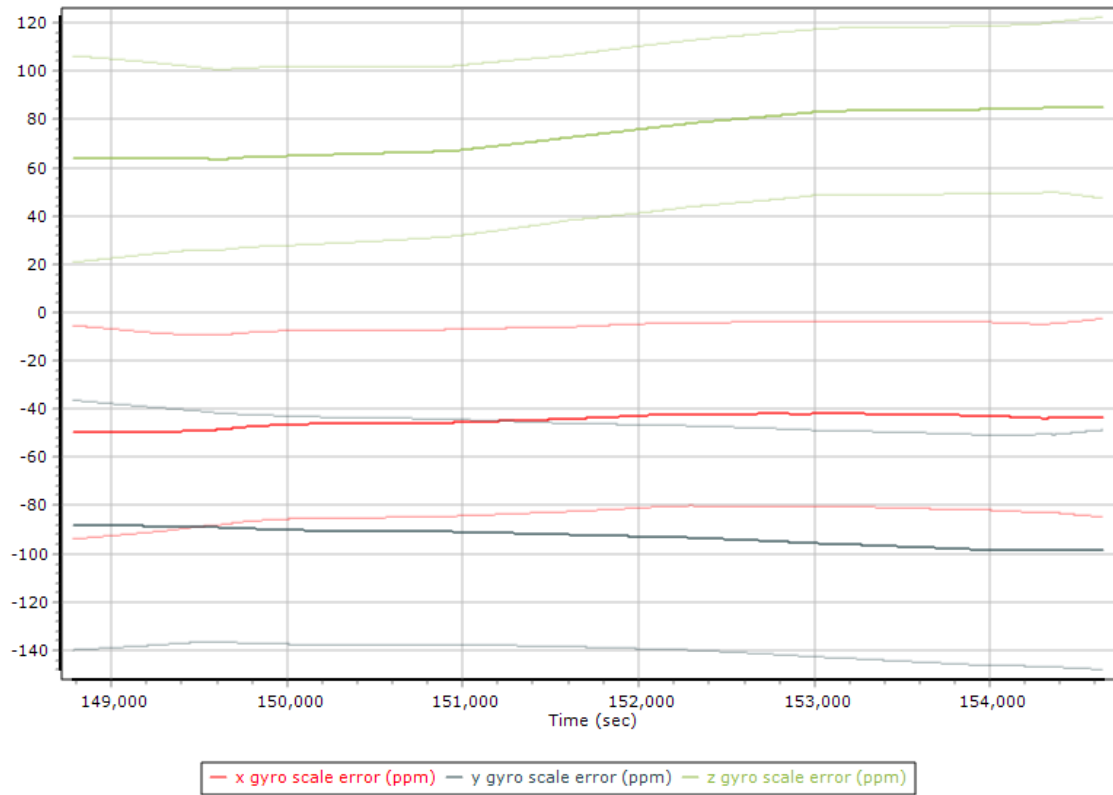




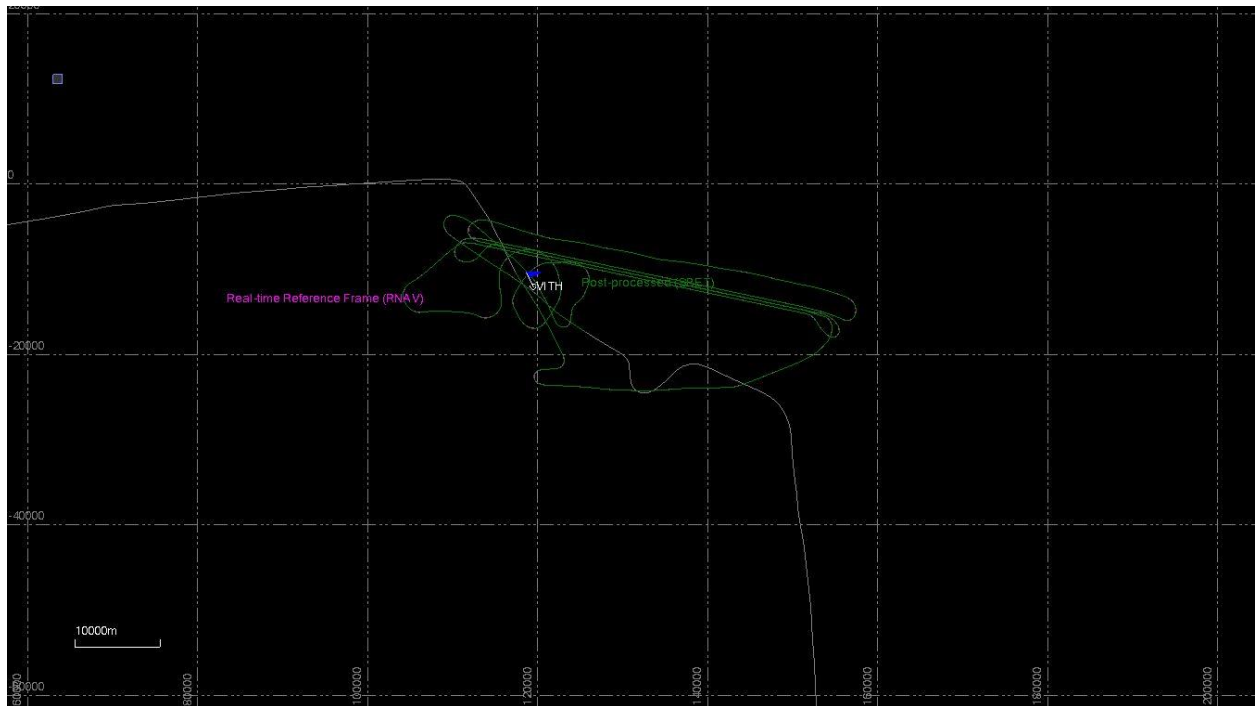
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



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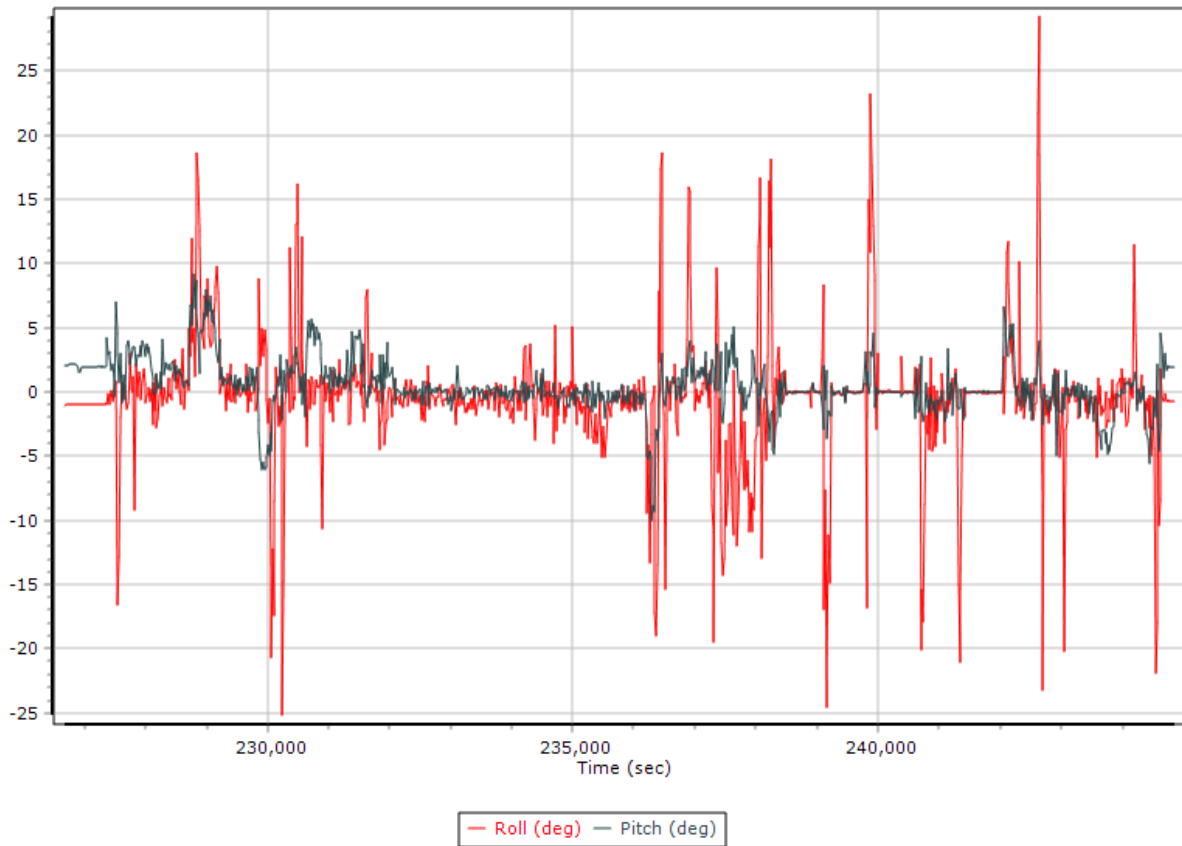
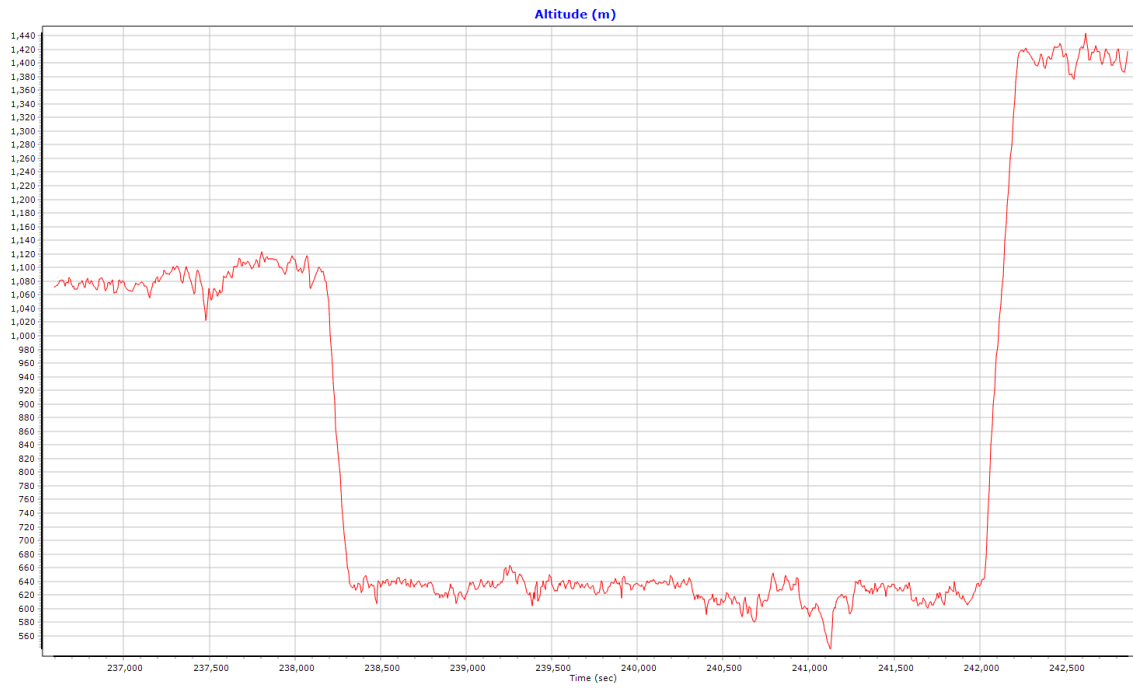


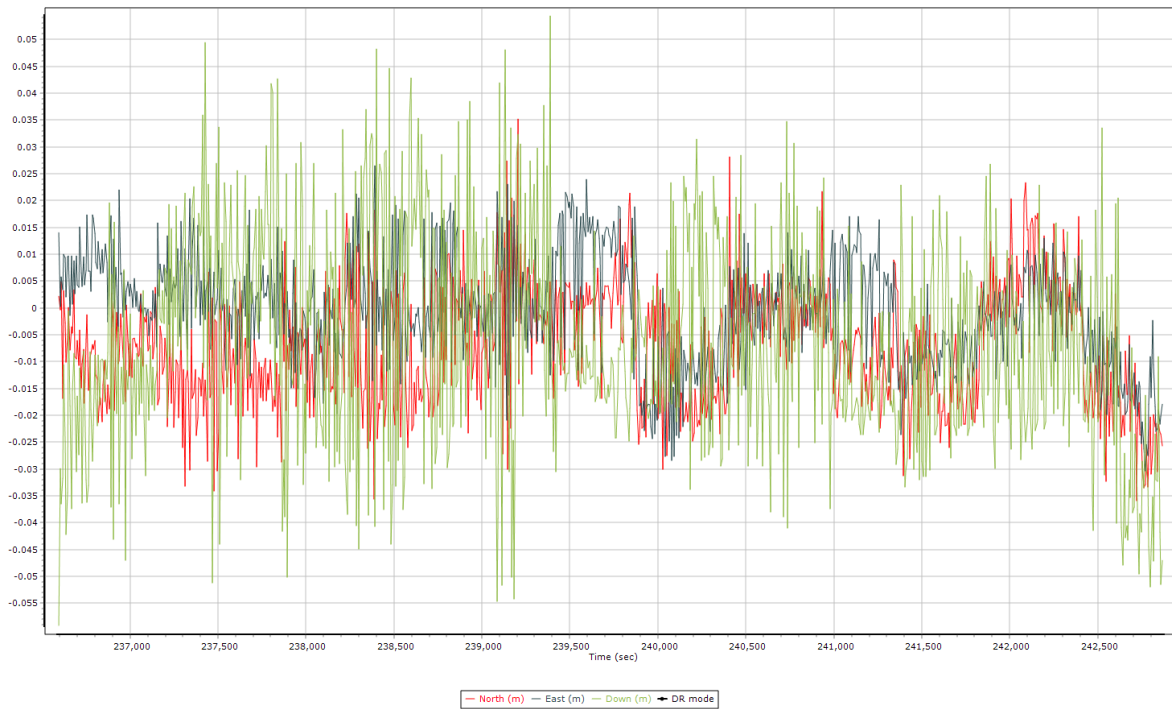
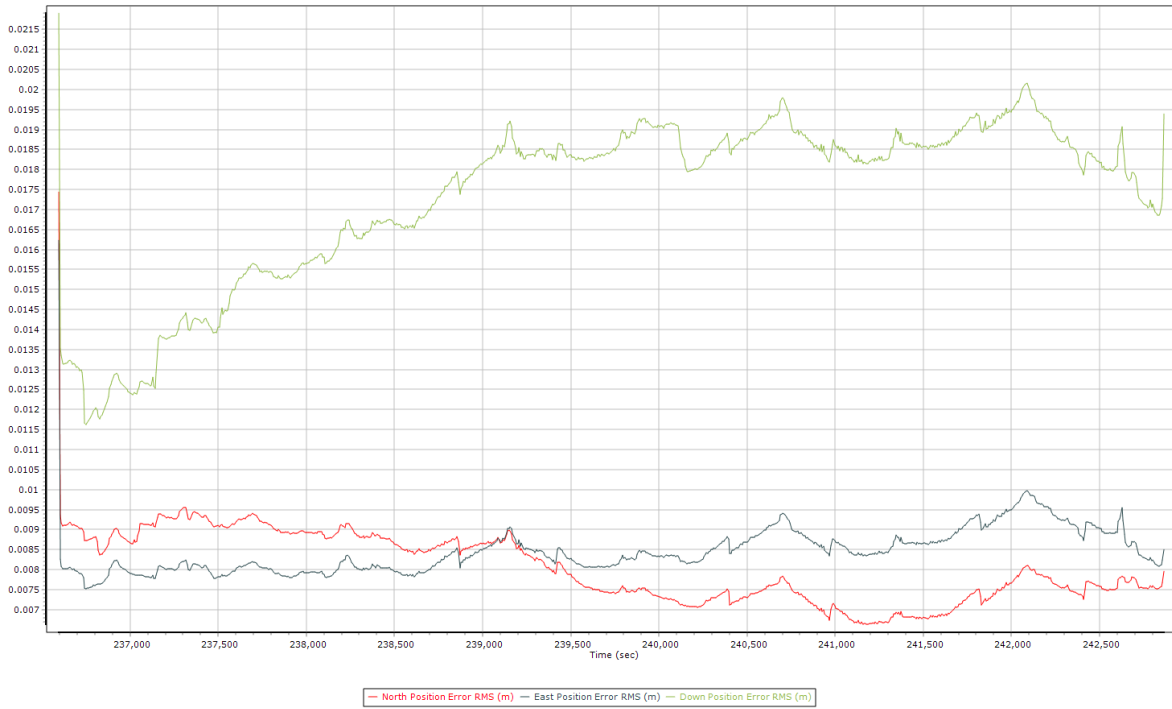
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 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		

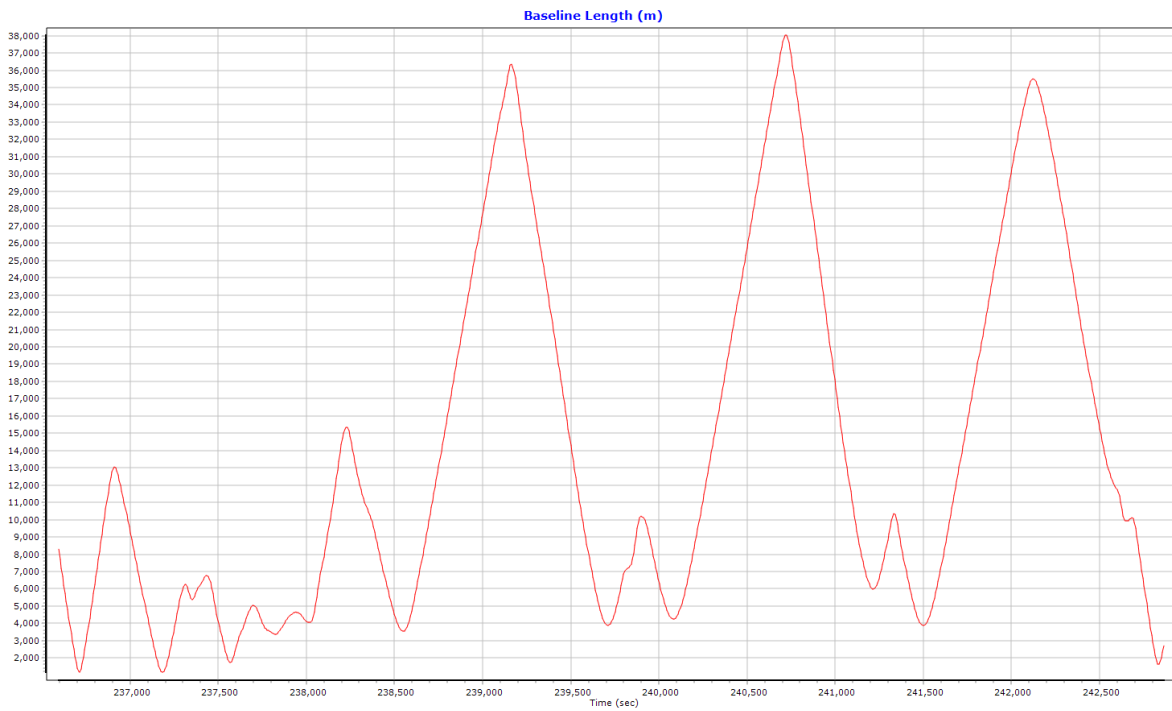
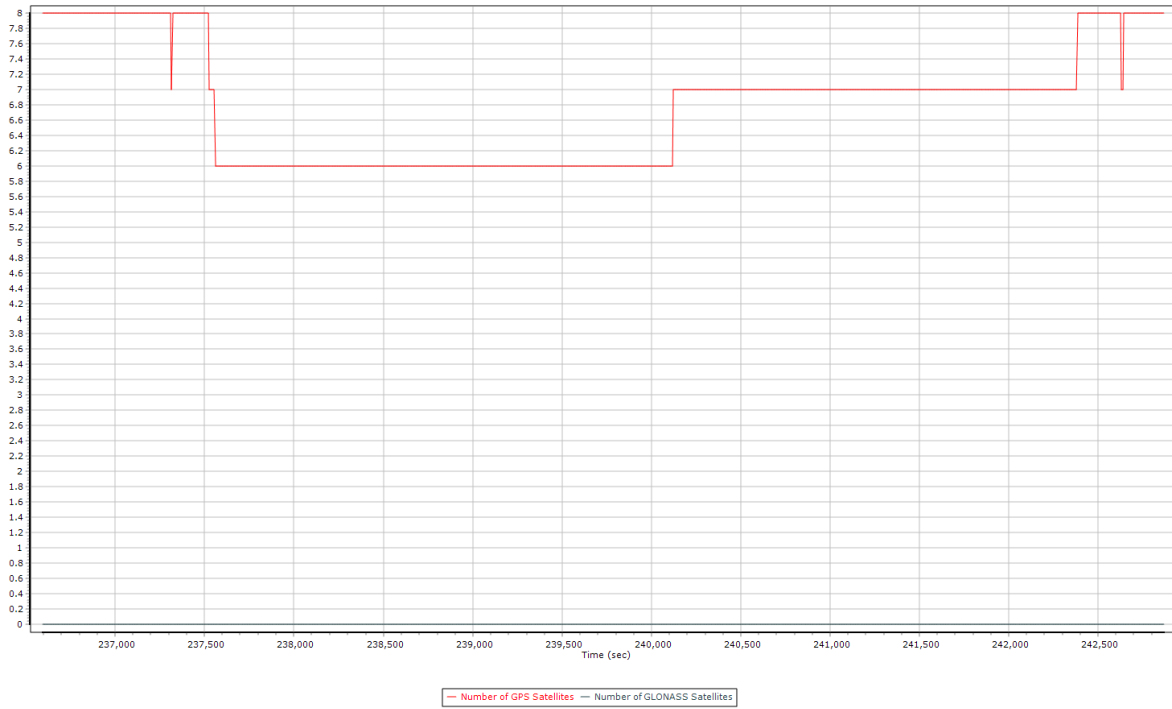
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

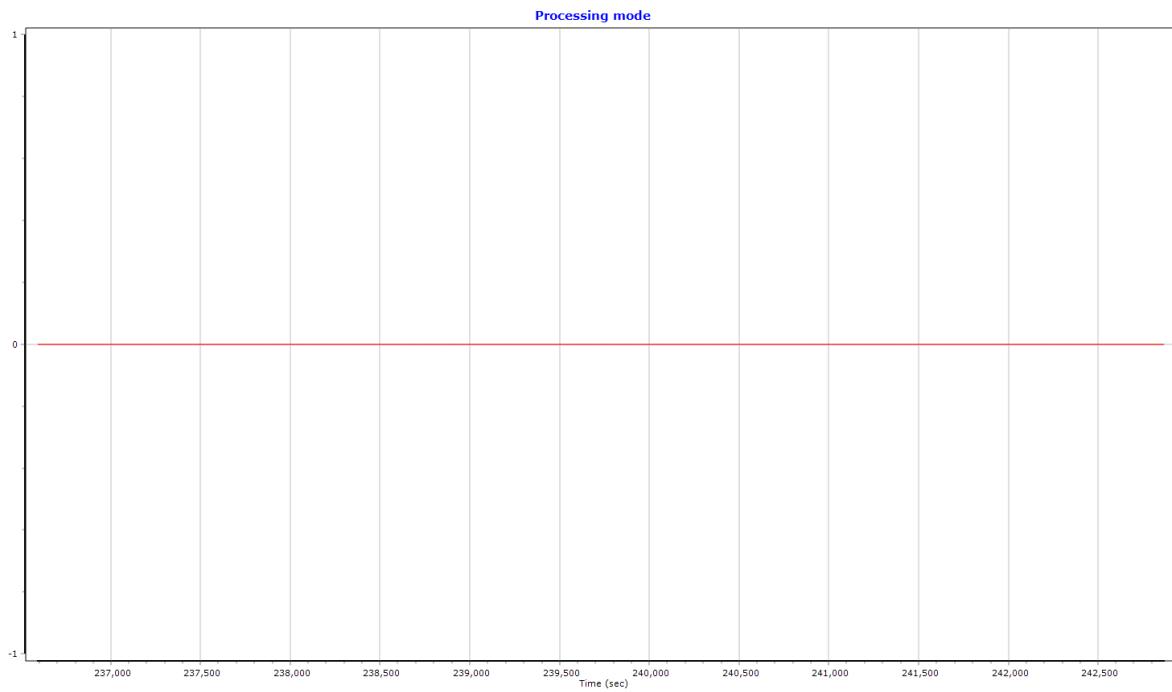
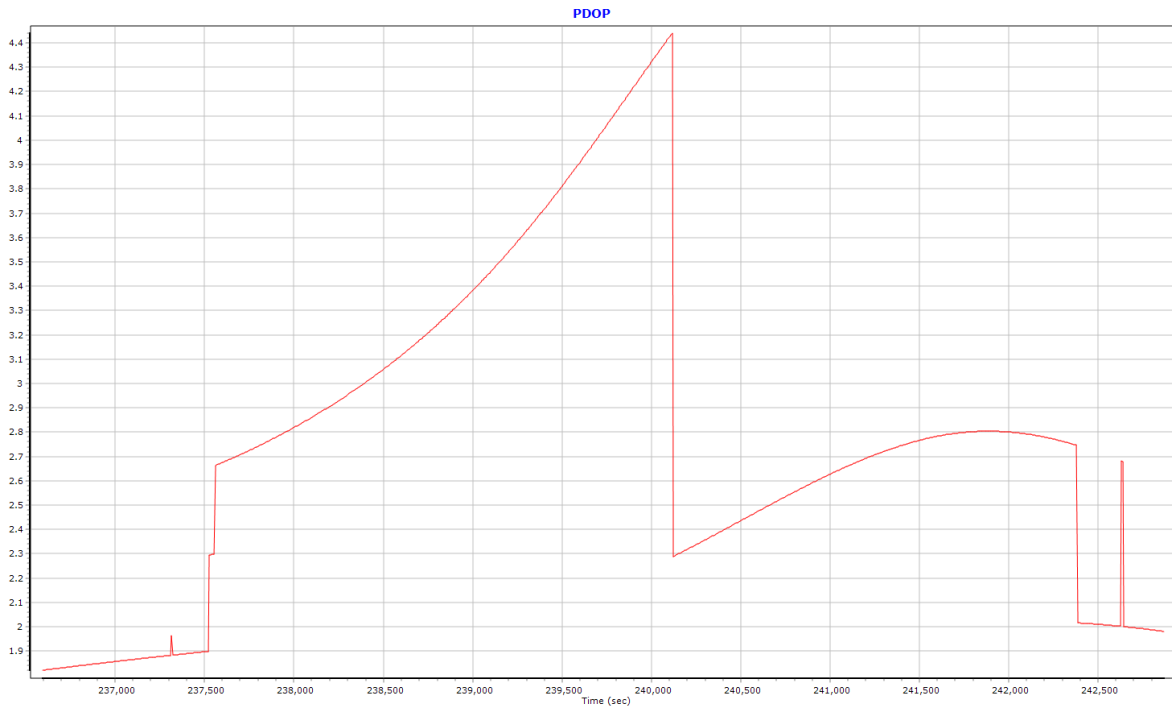
Timing	
Start	<input type="text" value="236592.406"/>
End	<input type="text" value="242873.621"/>
<input type="checkbox"/> Entire time interval <input checked="" type="checkbox"/> Seconds of start week	
UTC Offset	<input type="text" value="18.000"/>

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



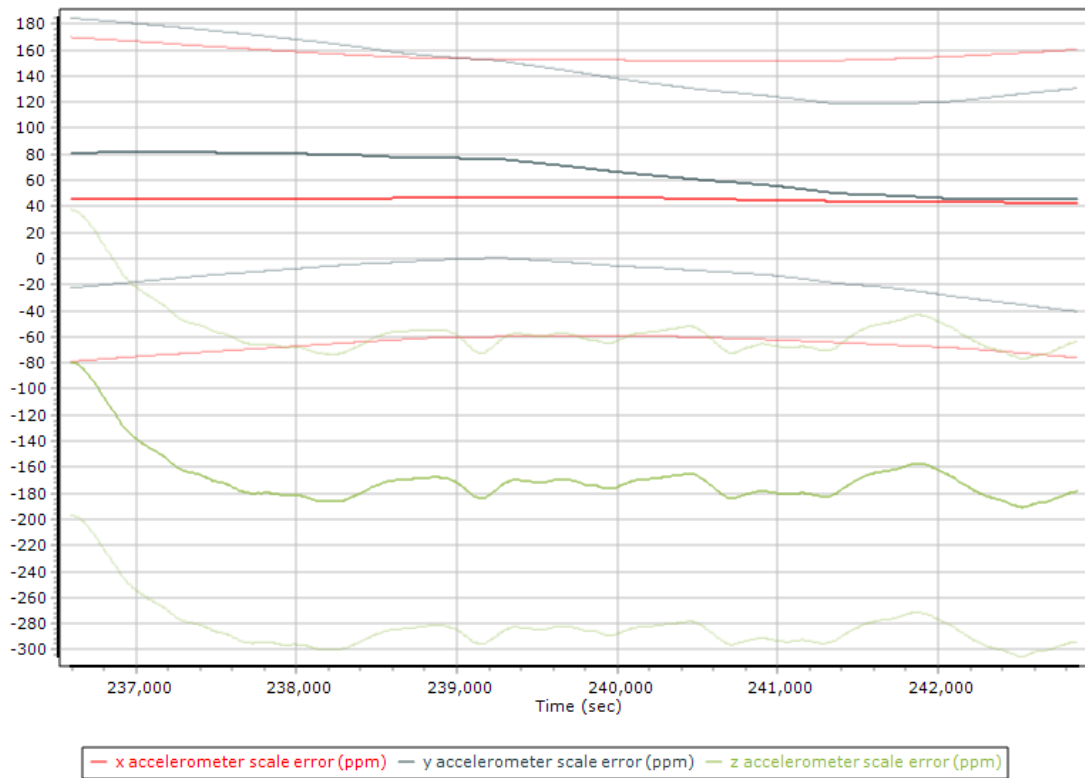
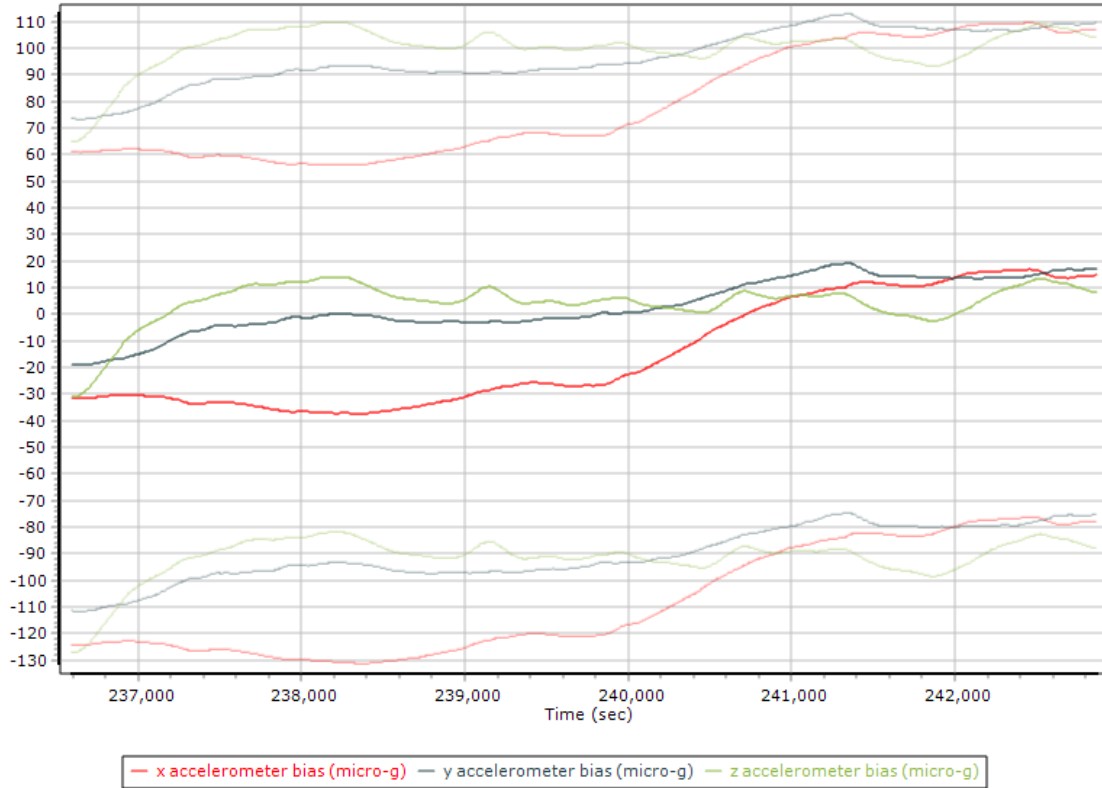


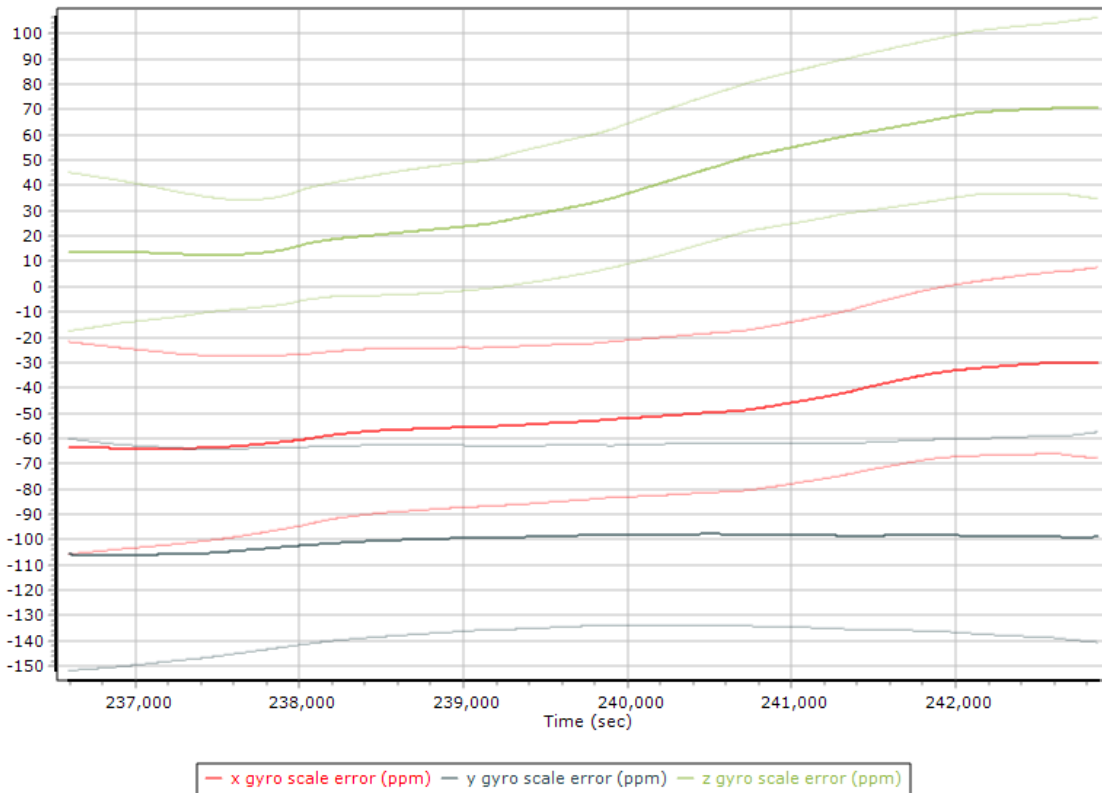
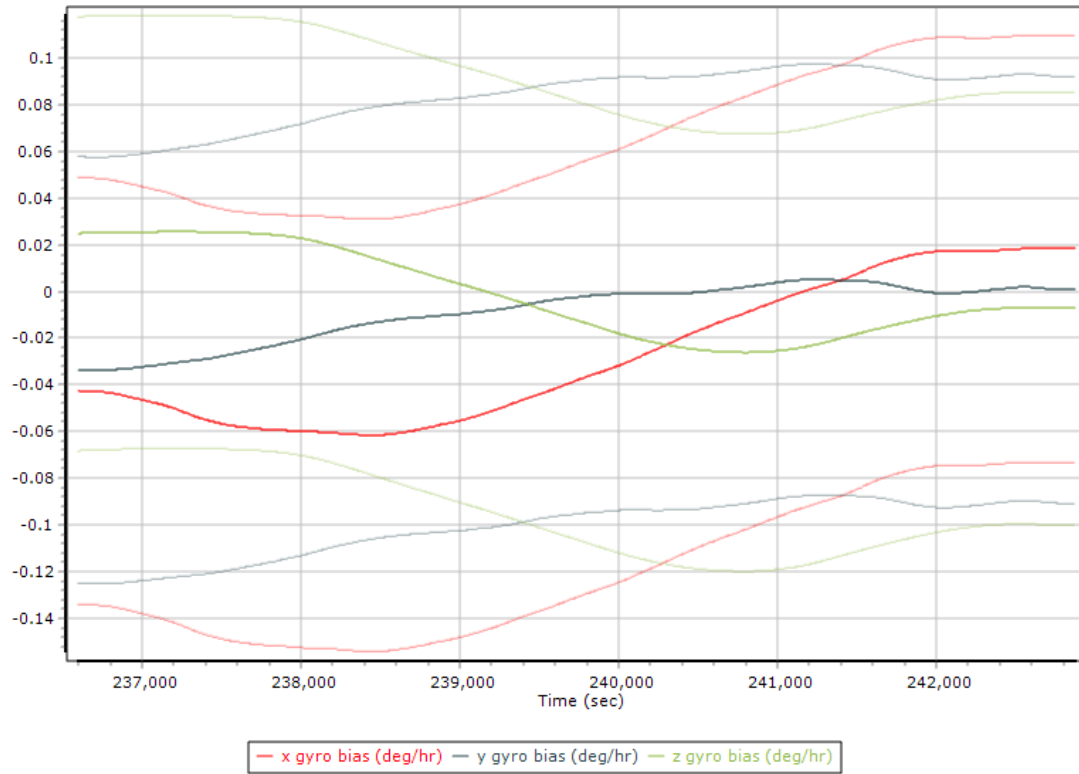




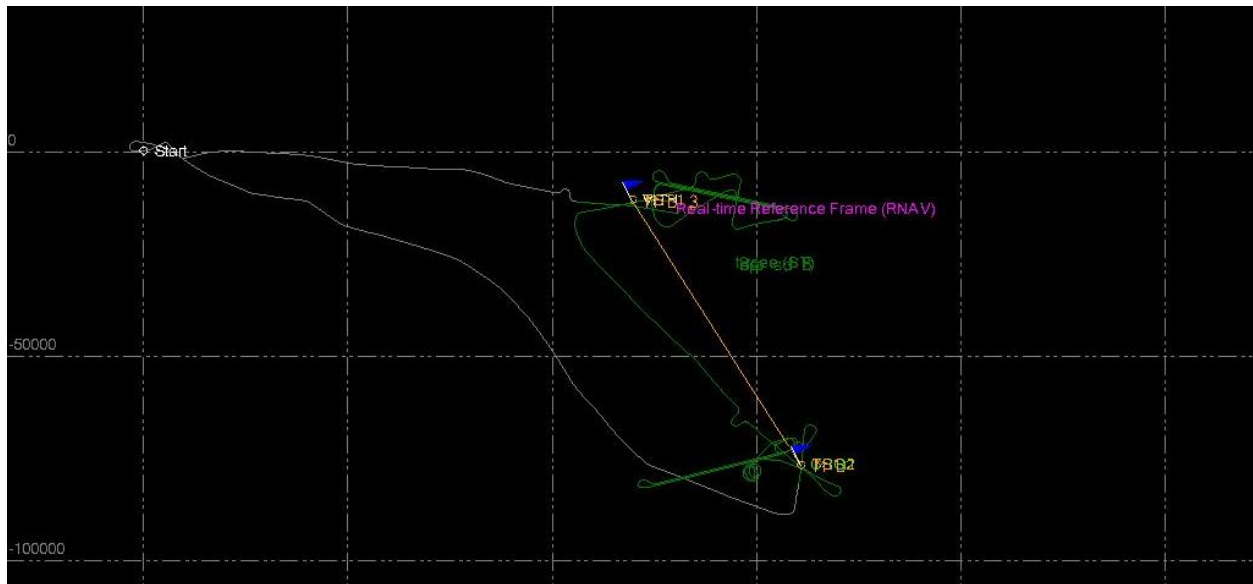
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





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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"/>

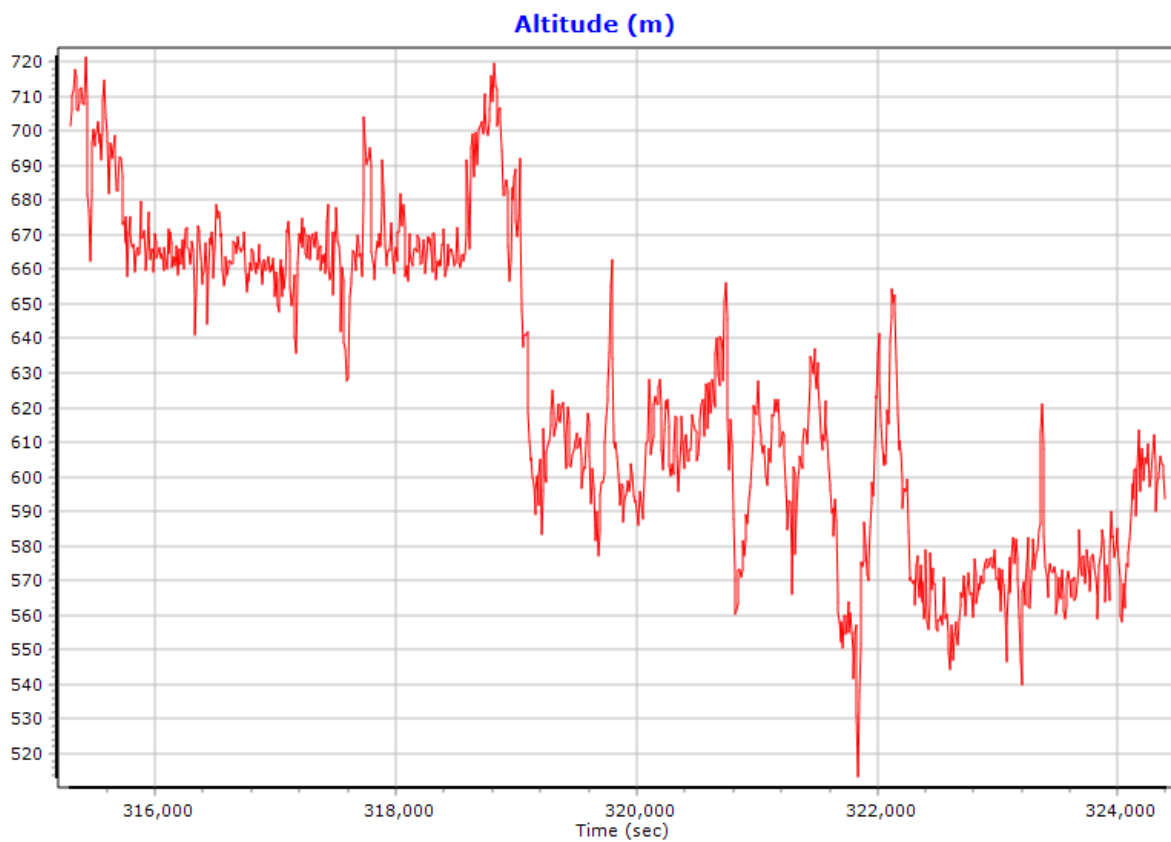
Standard Deviation 
<3cm 10cm 50cm 1m 10m

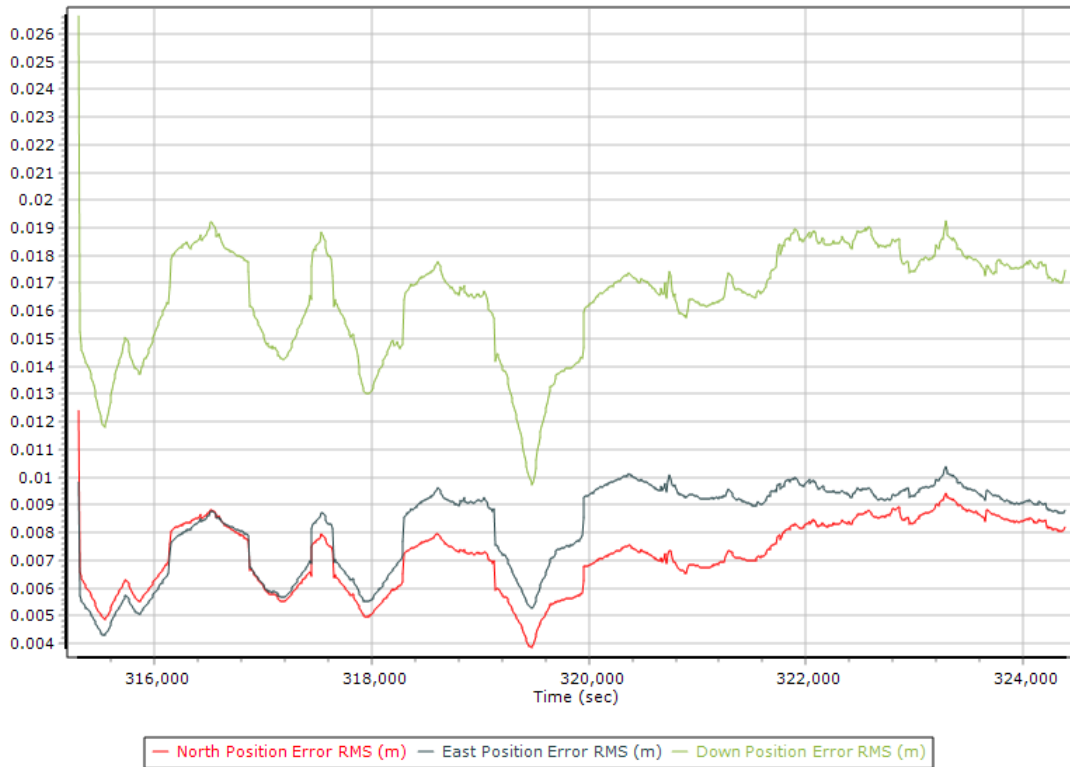
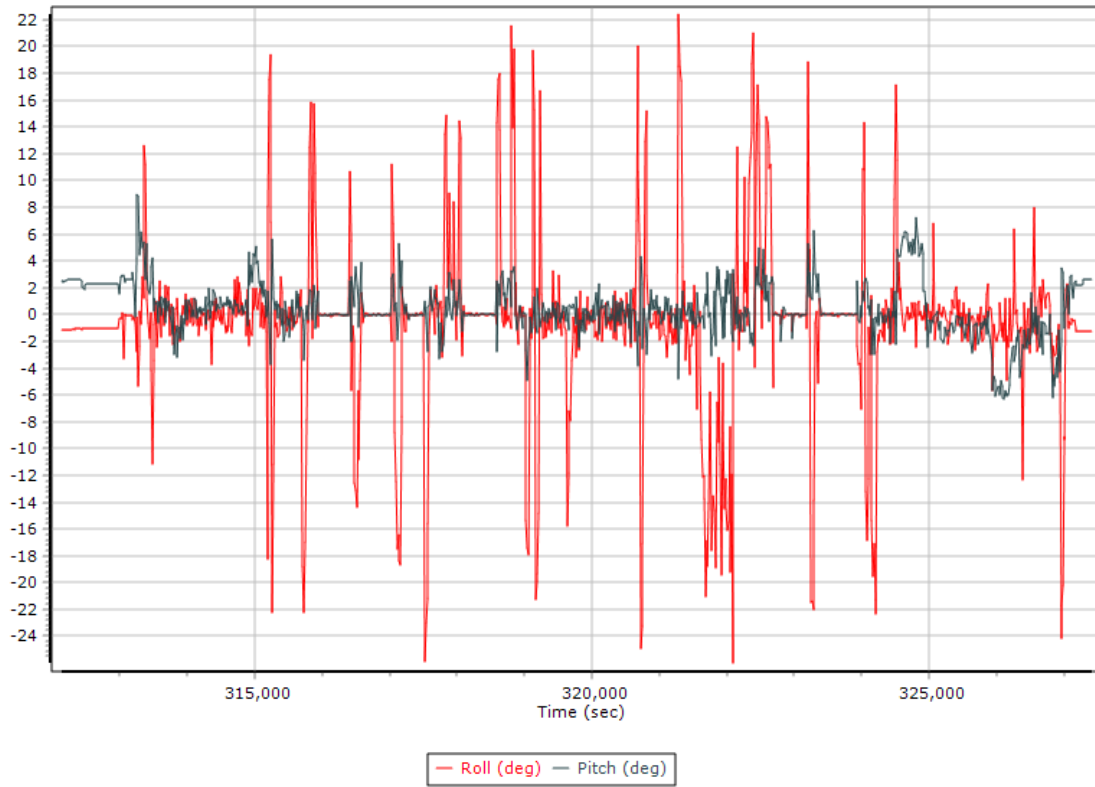
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

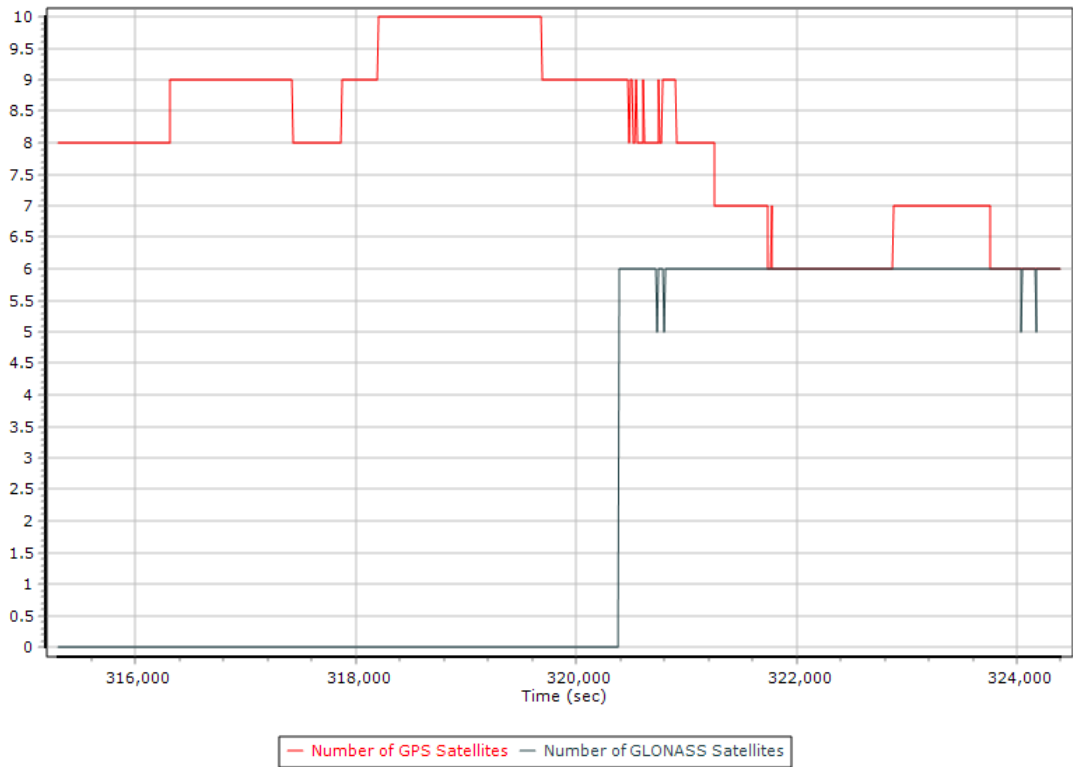
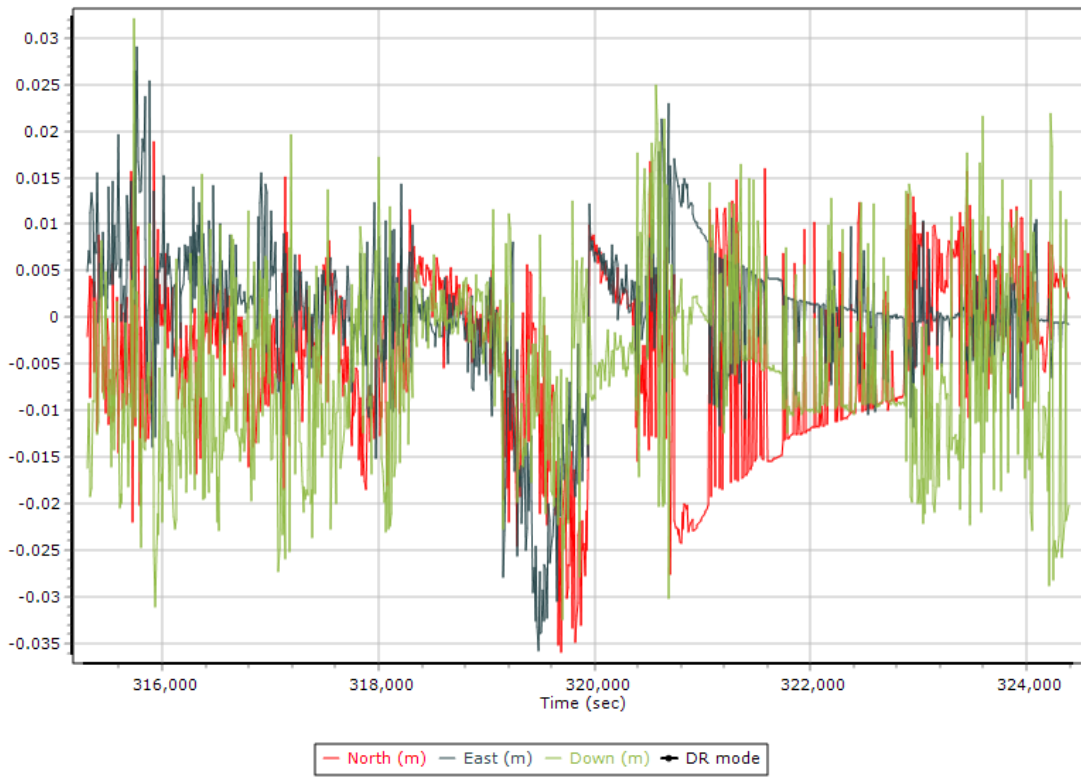
Timing

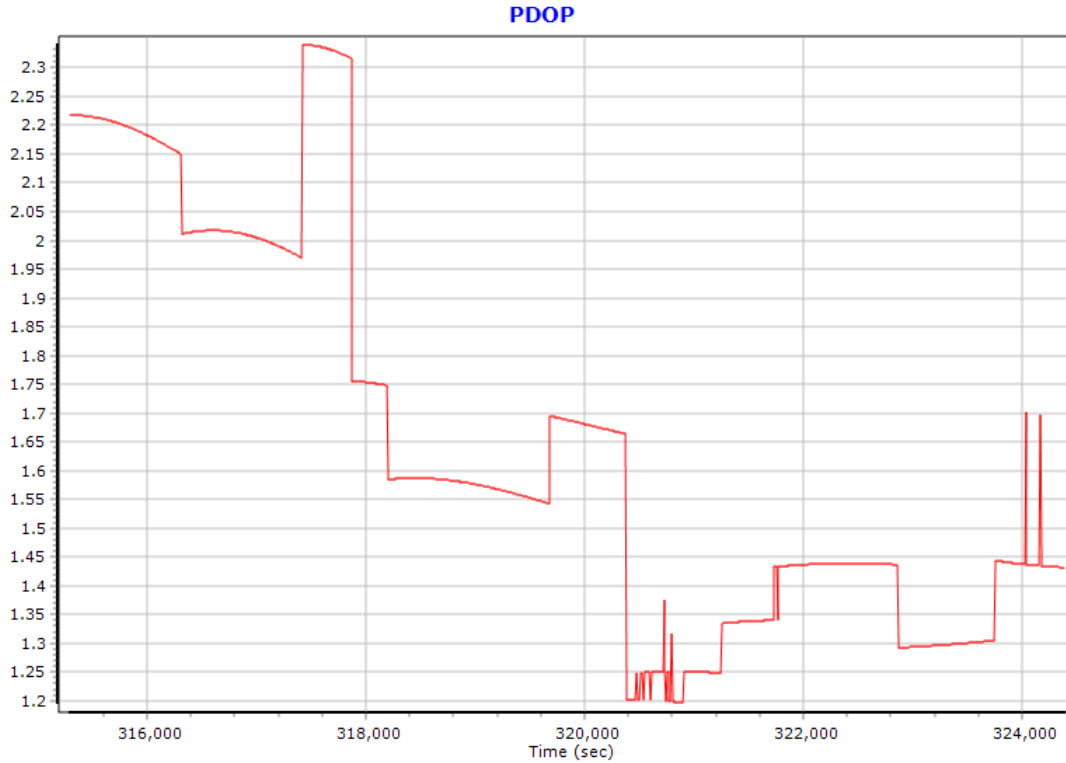
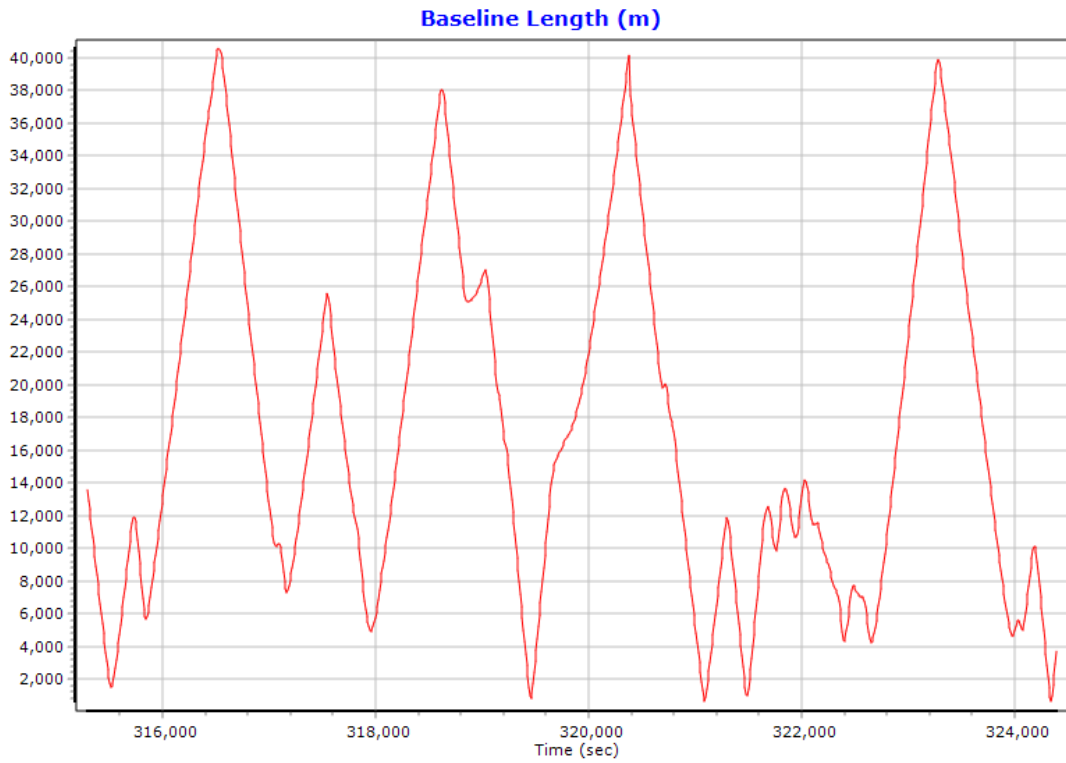
Start	<input type="text" value="315295.589"/>	Data	Incr. (sec)
End	<input type="text" value="324403.370"/>	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

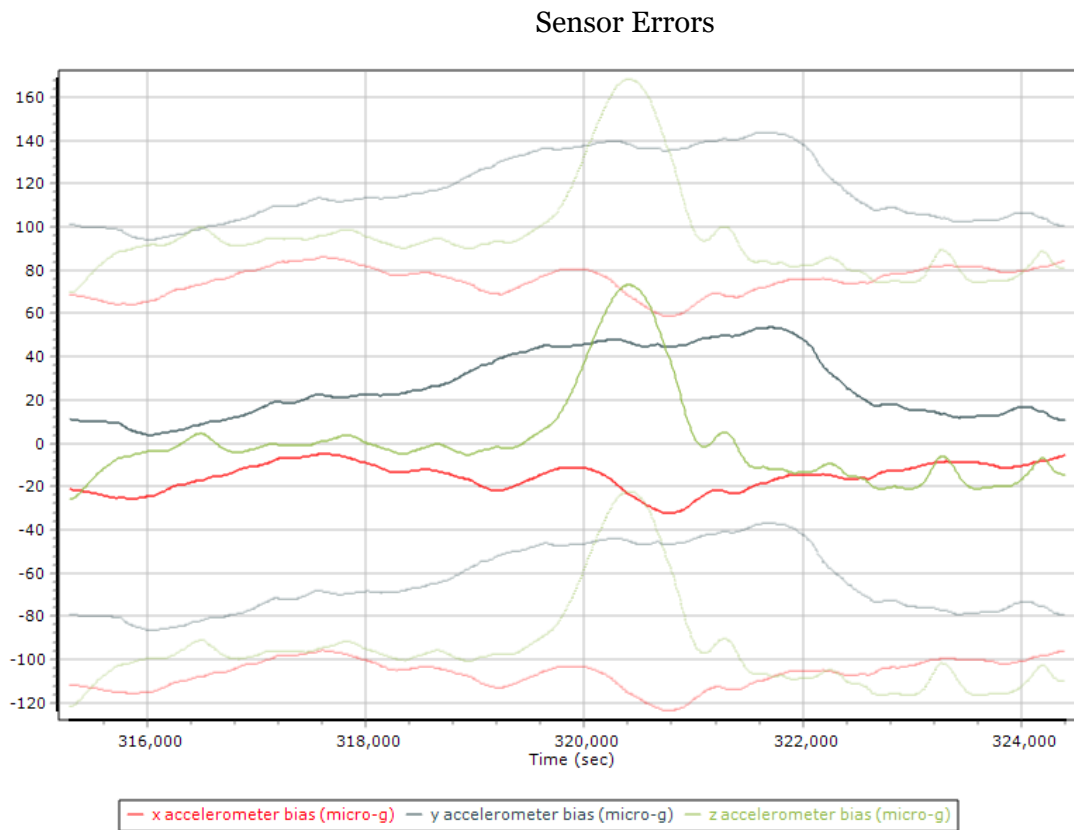
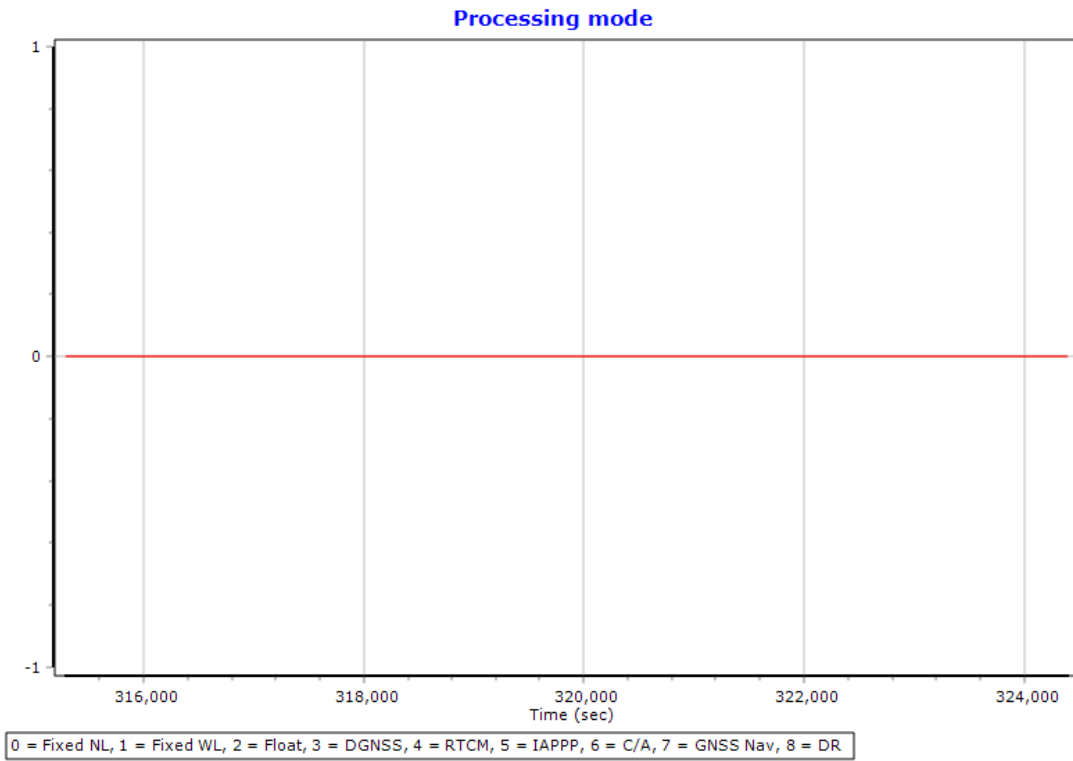
UTC Offset

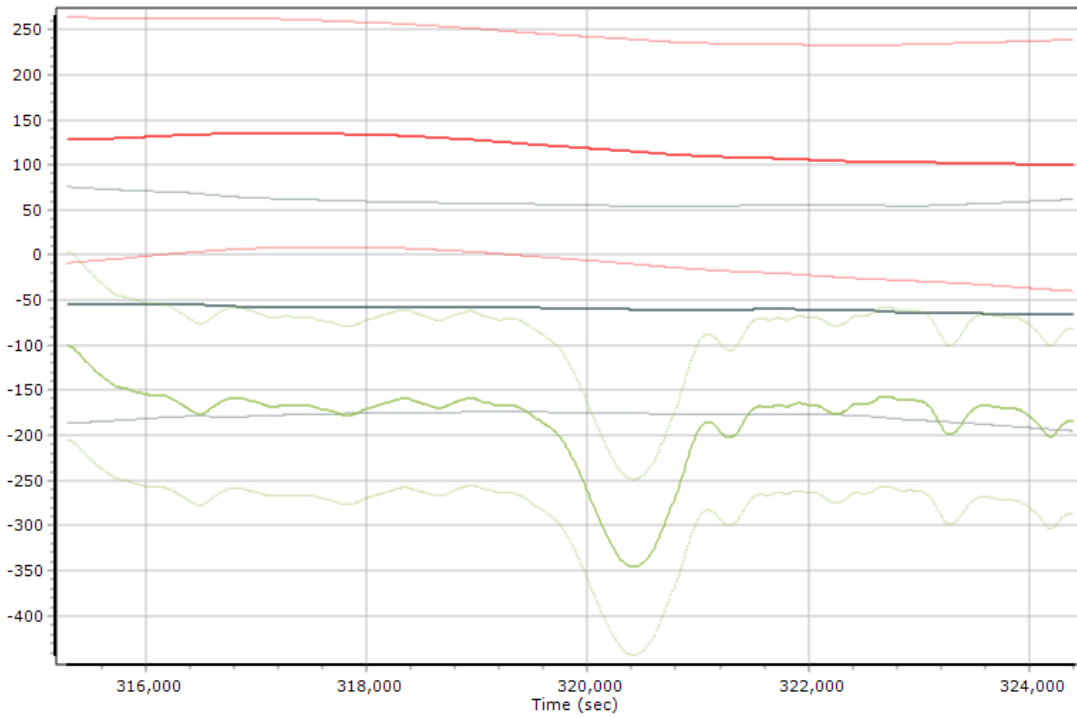




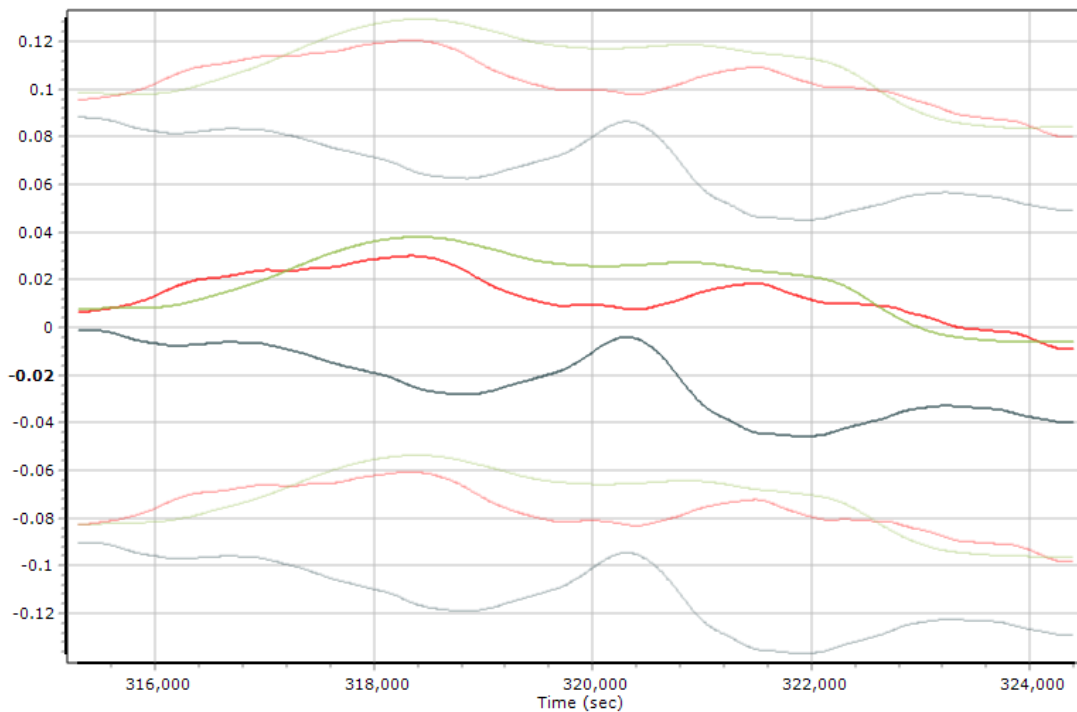




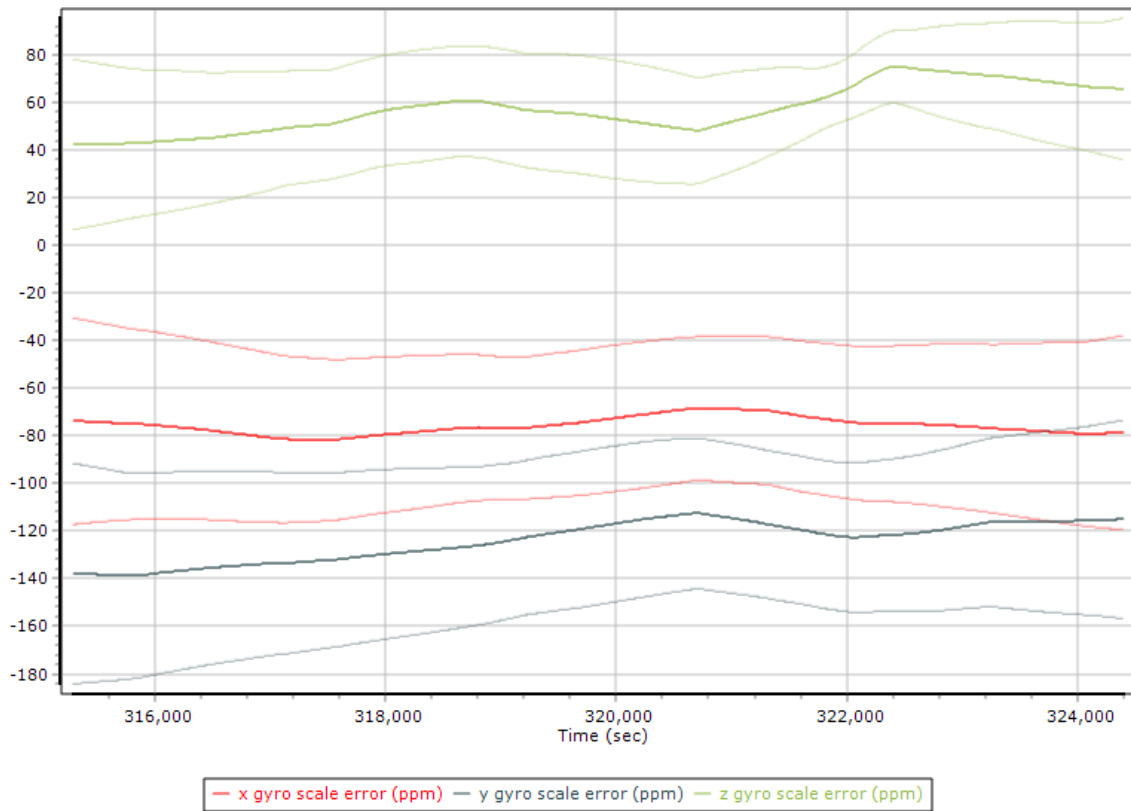




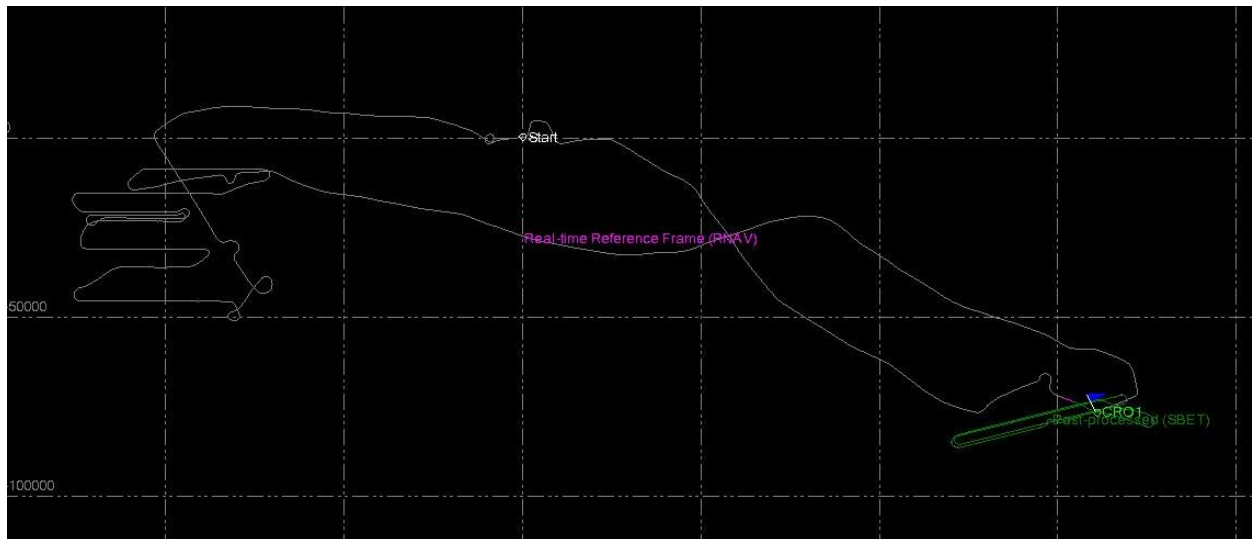
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

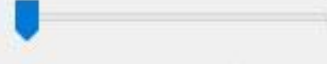


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

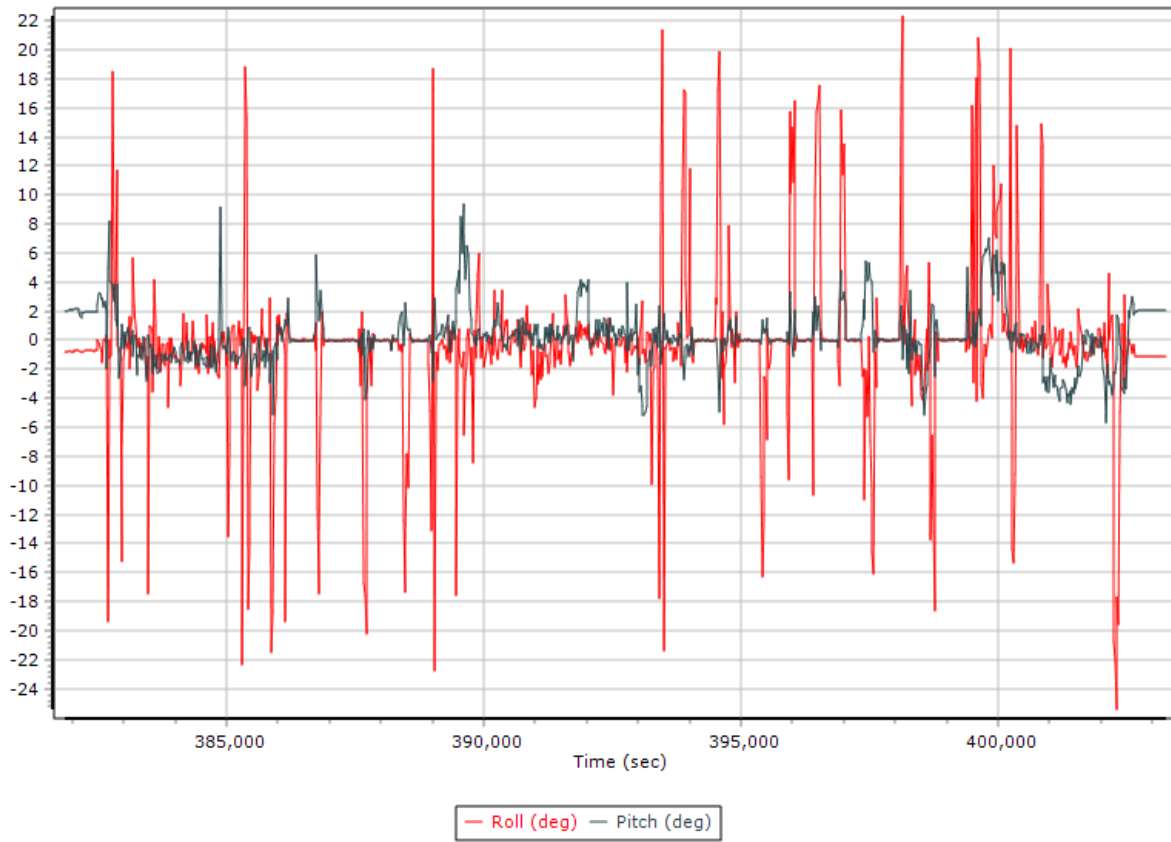
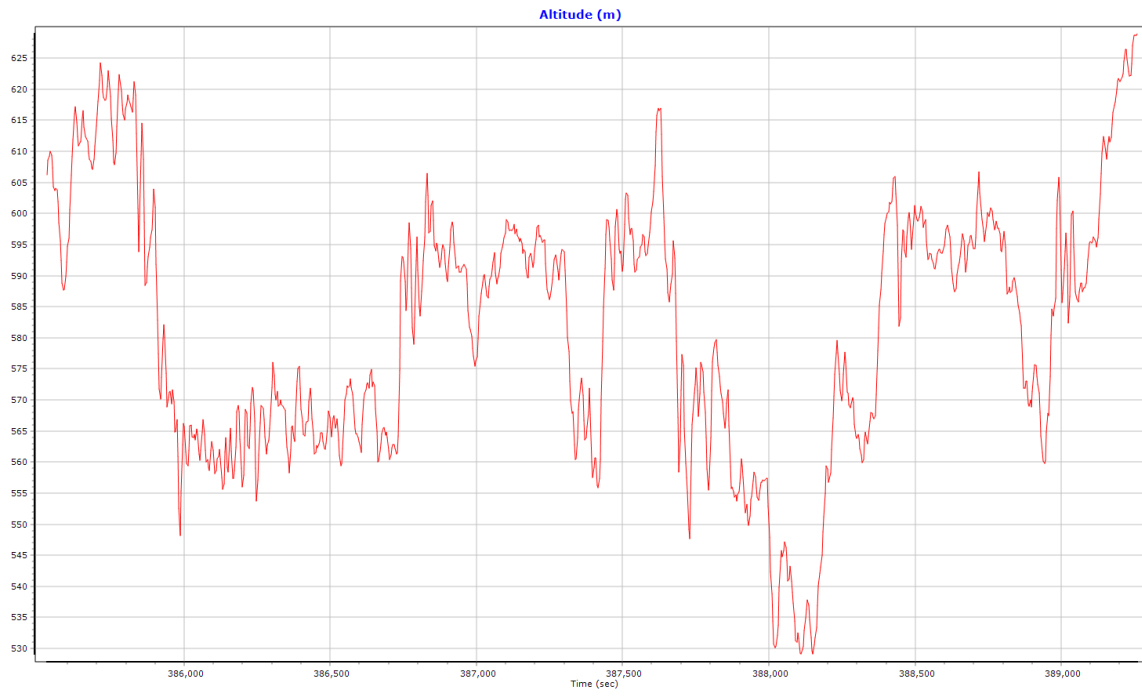


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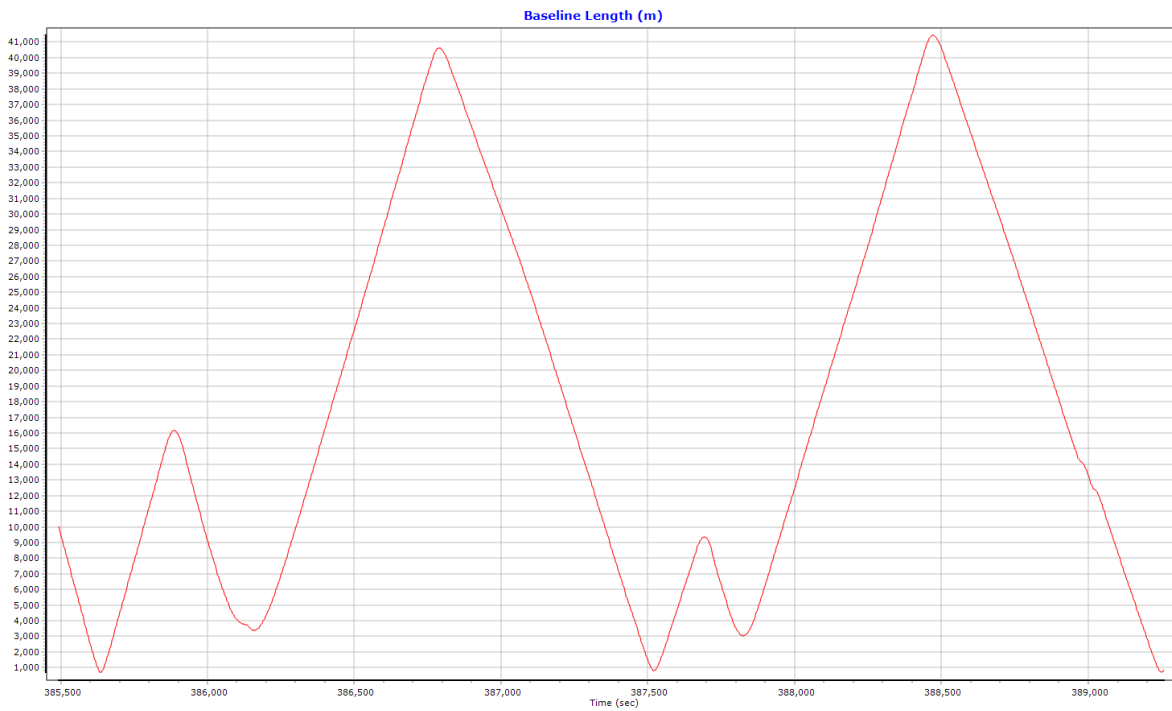
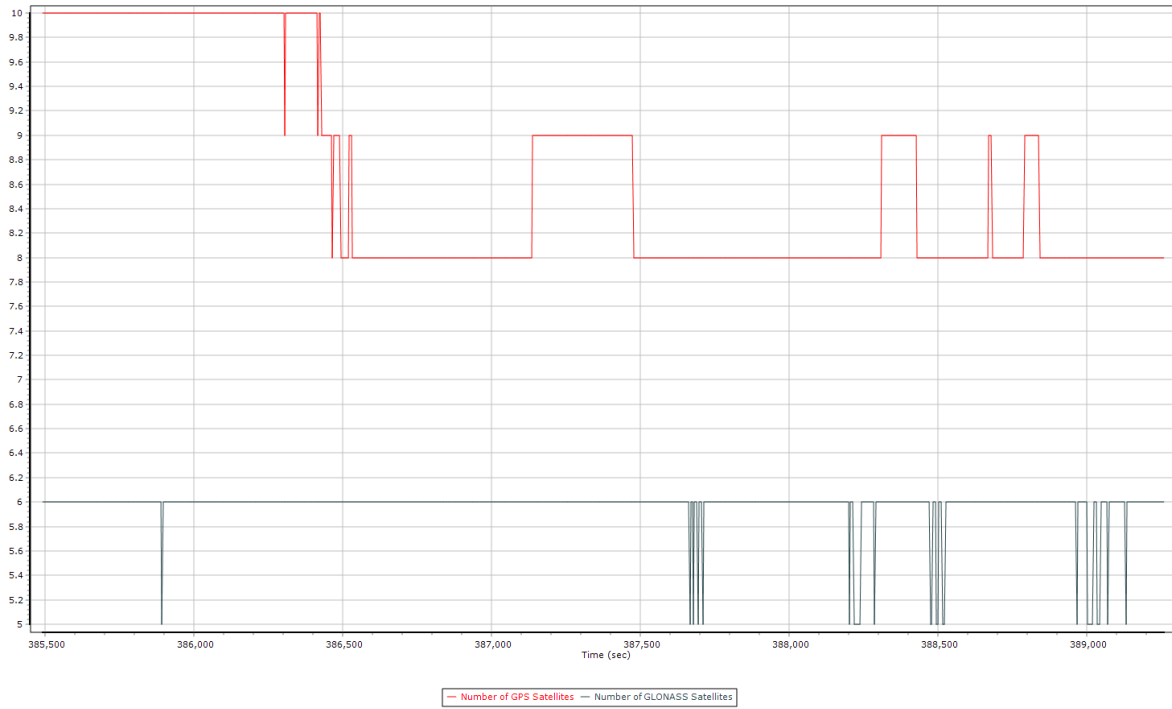


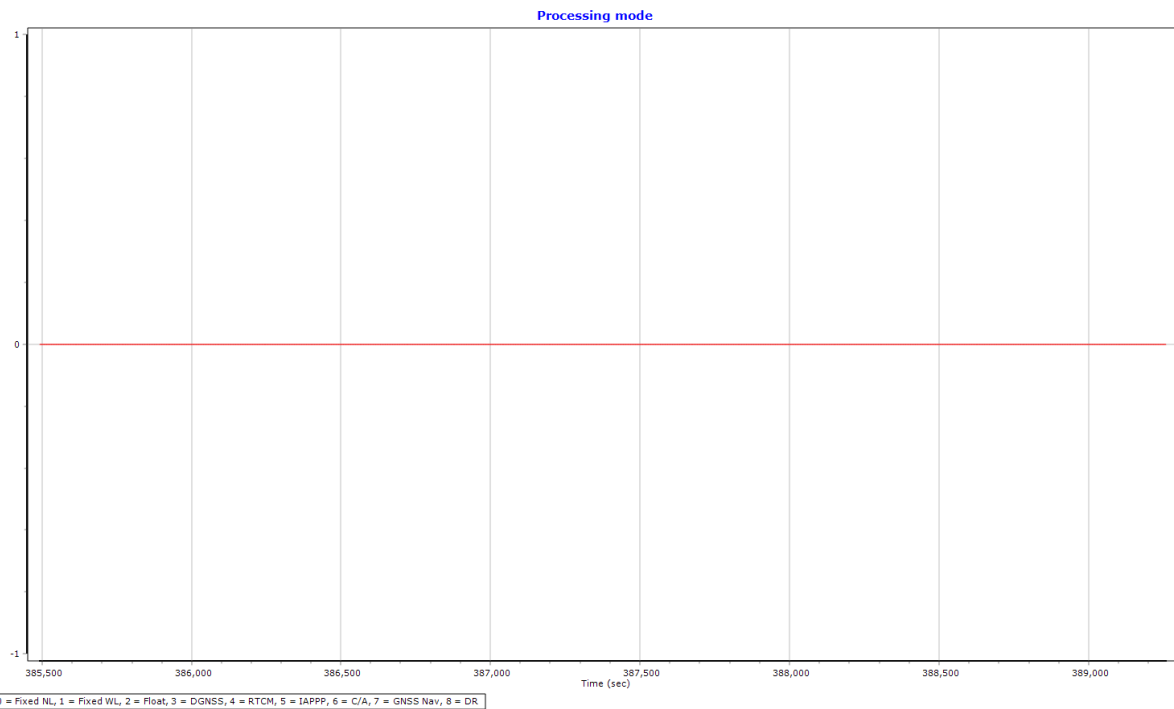
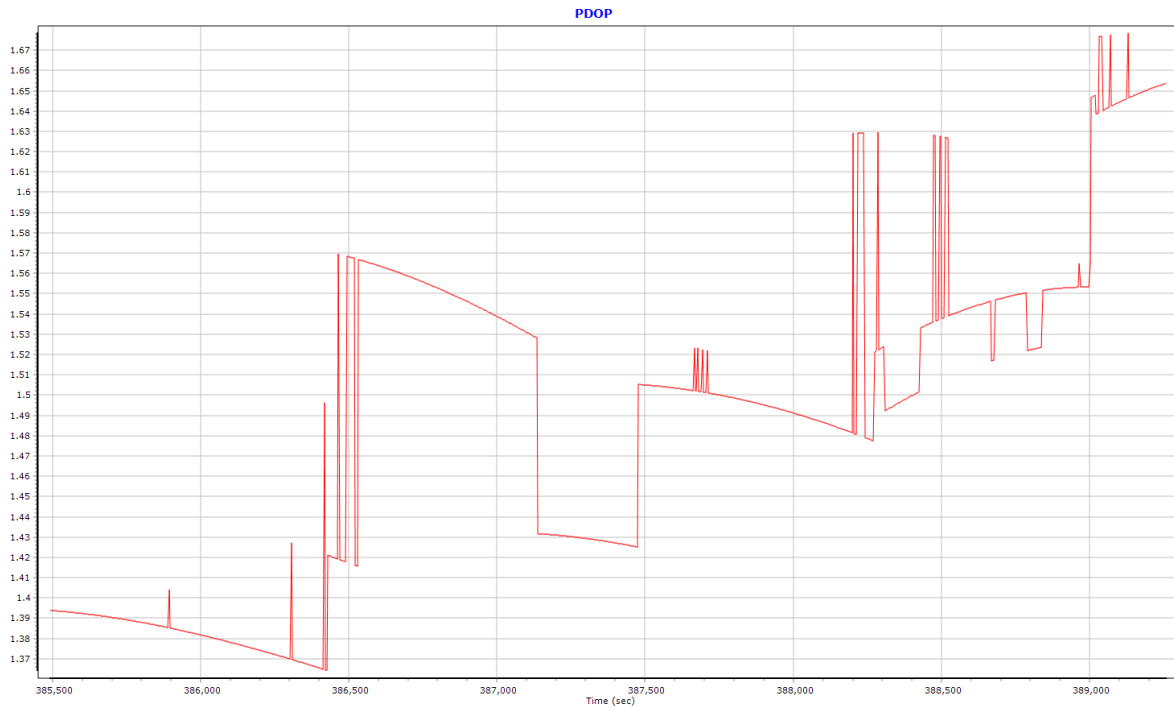
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000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

Timing			
Start	<input type="text" value="385481.435"/>	Data	Incr. (sec)
End	<input type="text" value="389262.167"/>	Output Record	0.005000
<input type="checkbox"/> Entire time interval <input checked="" type="checkbox"/> Seconds of start week		IMU	0.005000
UTC Offset <input type="text" value="18.000"/>		Primary GNSS	1.000000

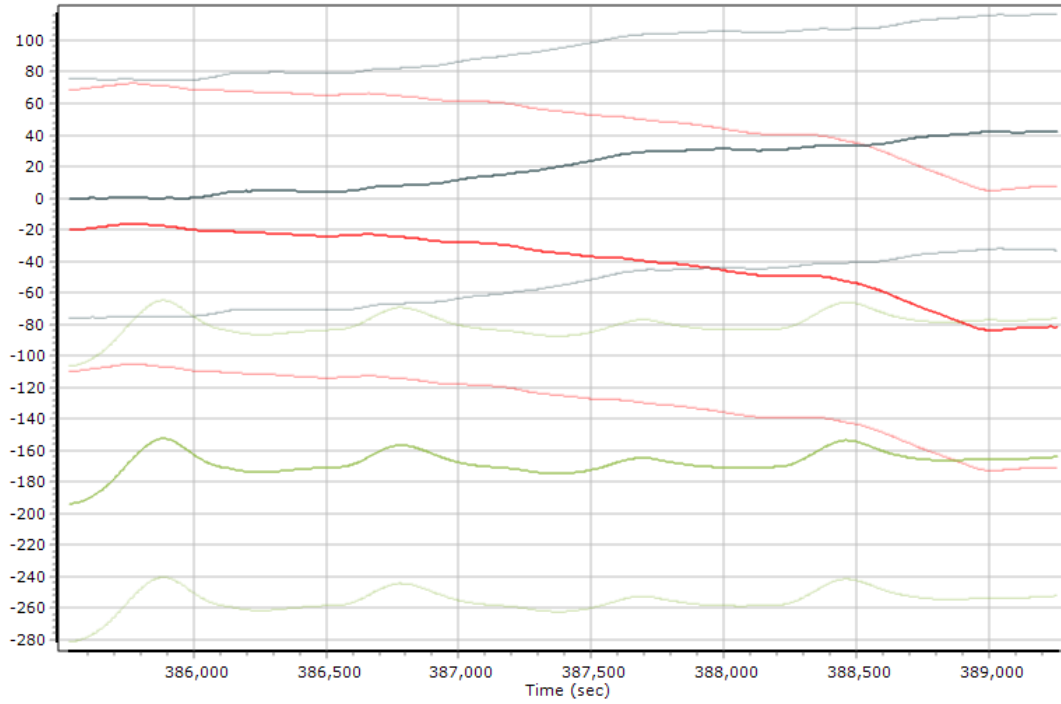




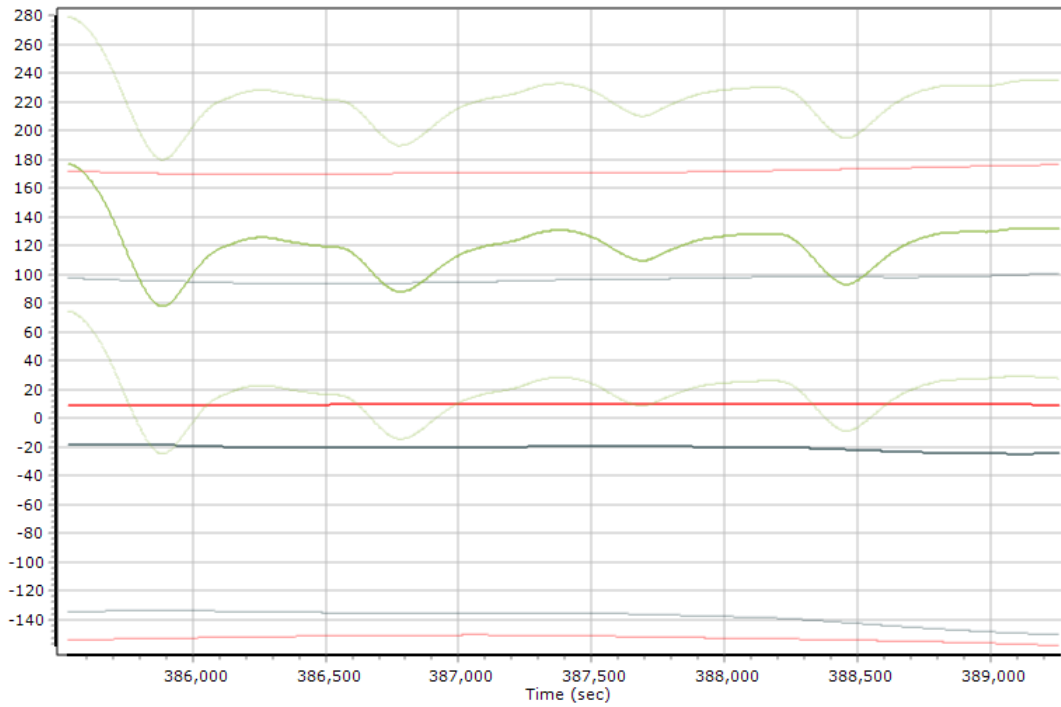




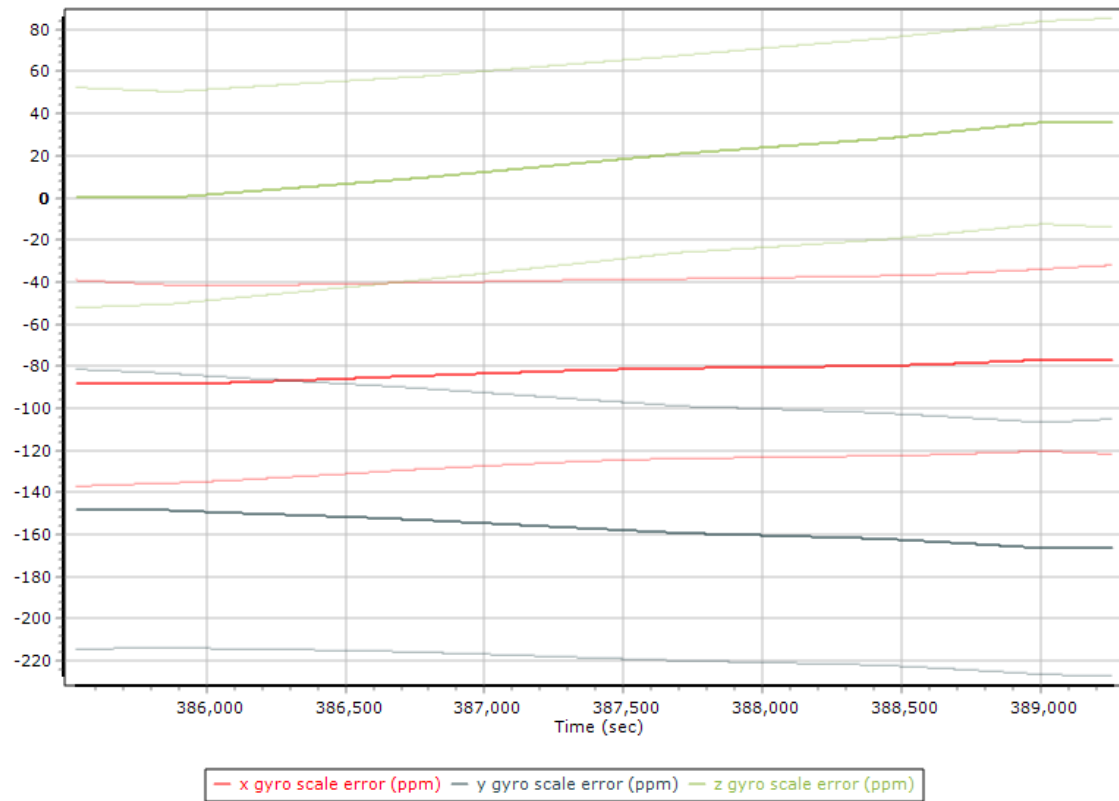
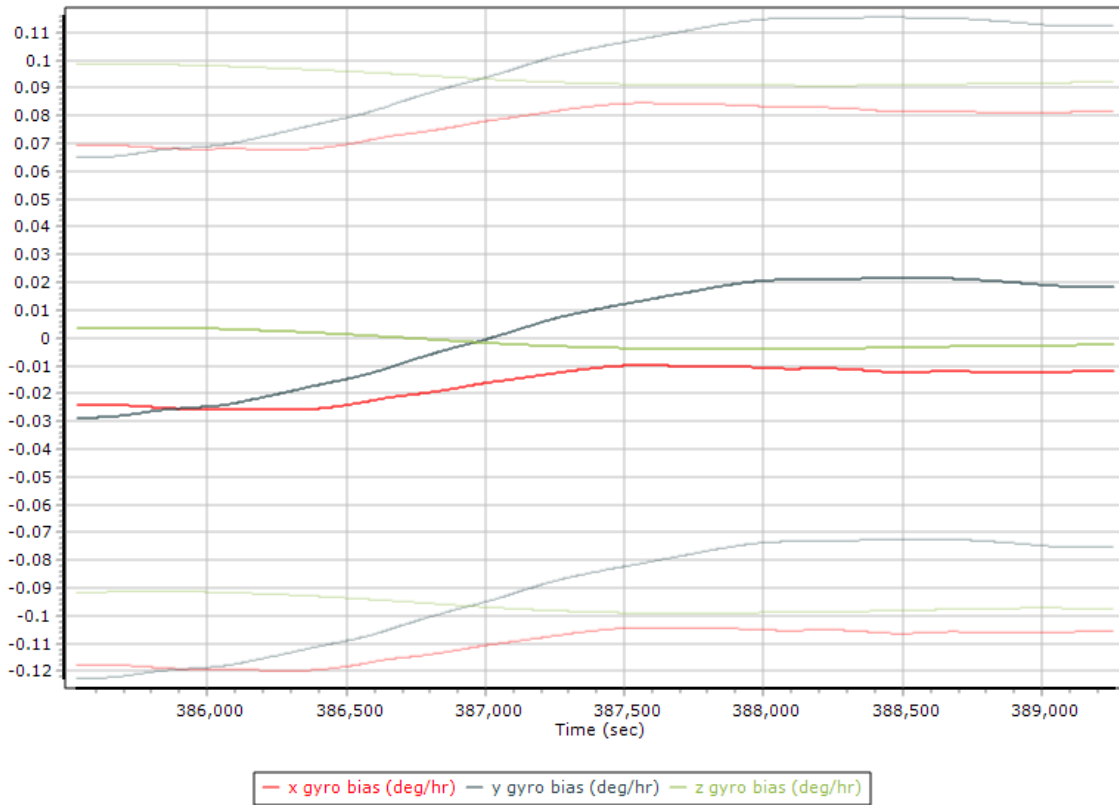
Sensor Errors



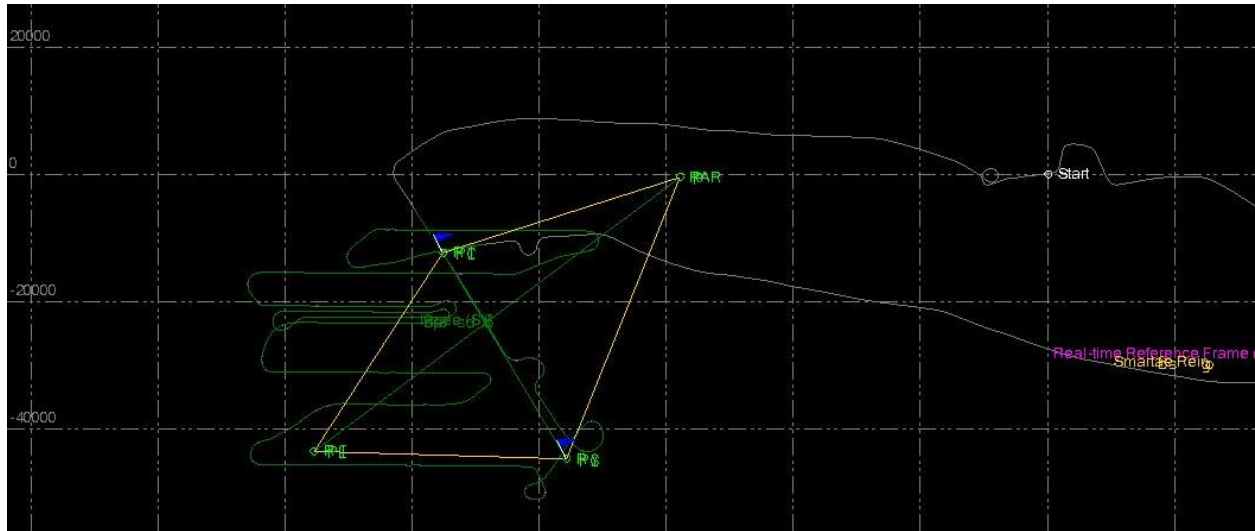
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



45A18284A2



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
 - Lever Arms and Mounting Angles
- Export
- Camera
- LIDAR
- SAR

Timing

Start: 393583.008

End: 400764.403

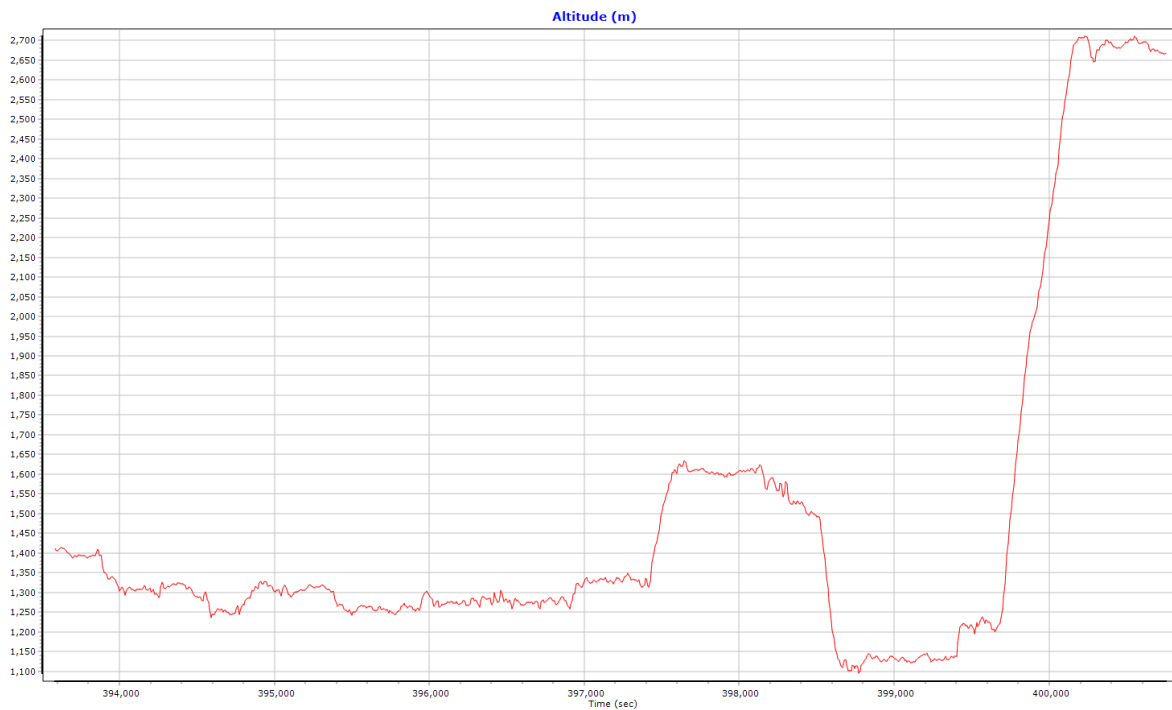
Entire time interval

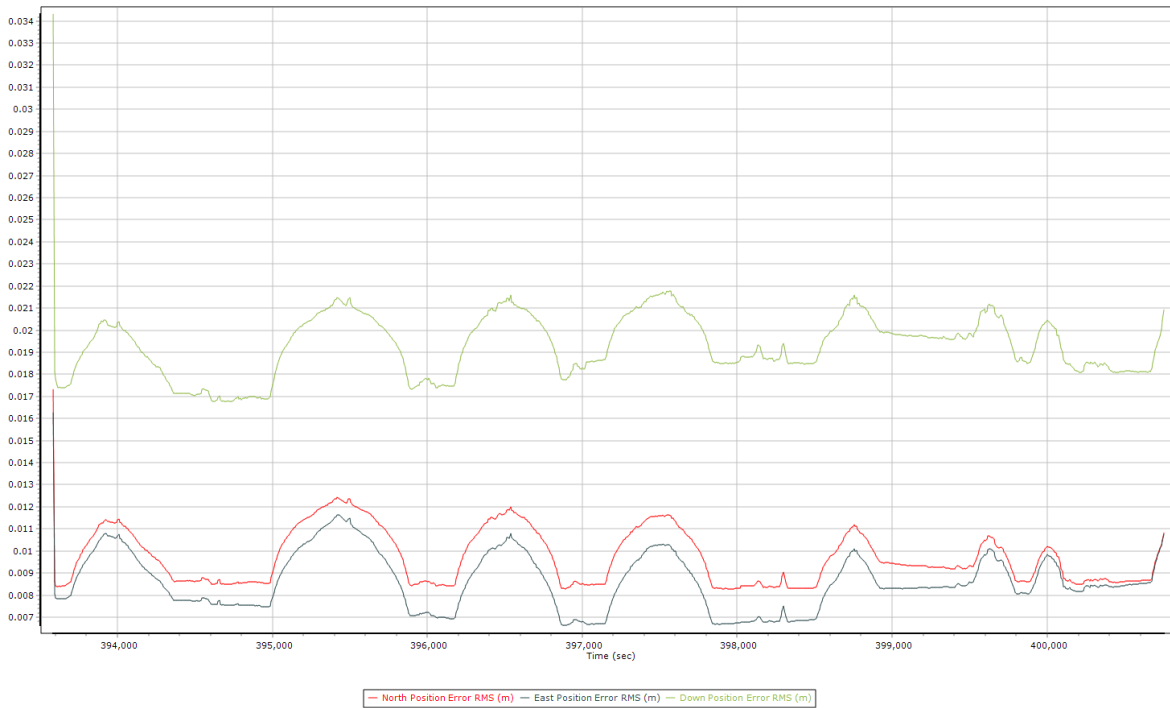
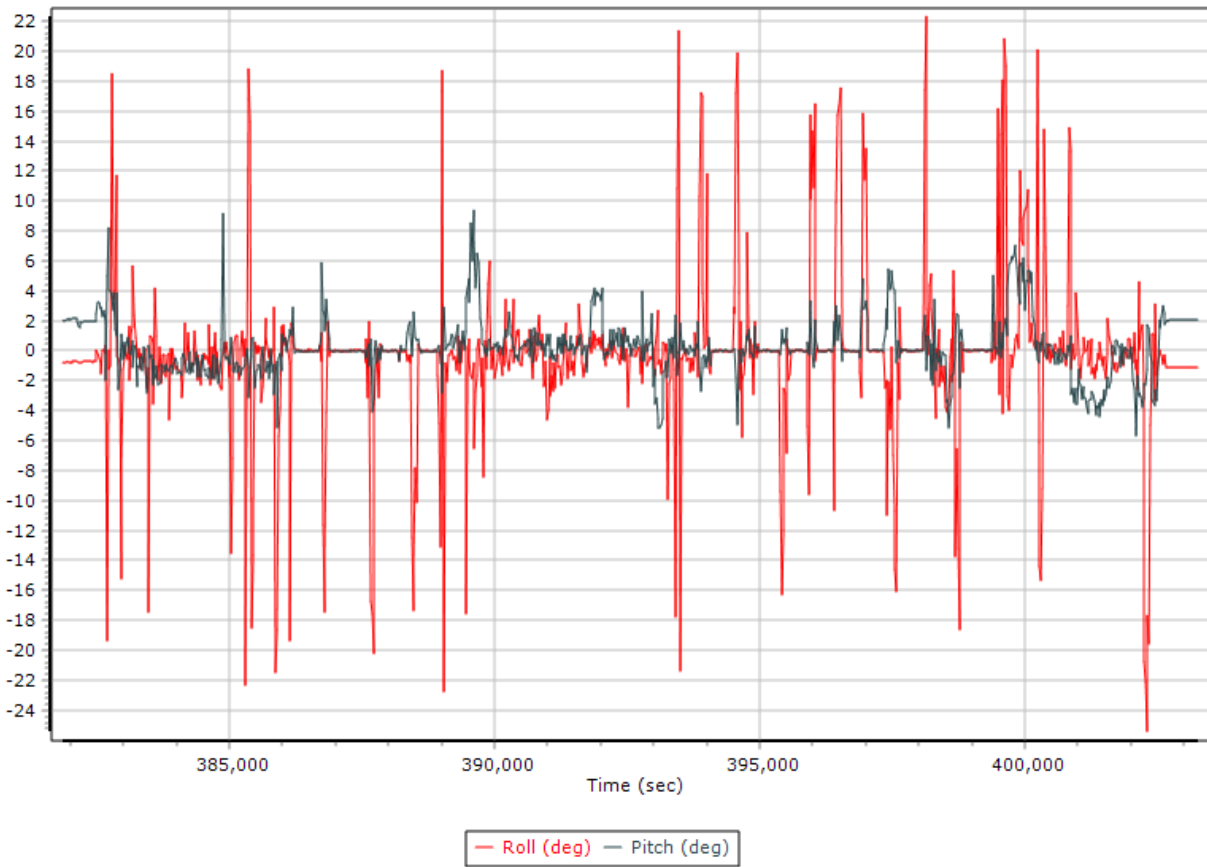
Seconds of start week

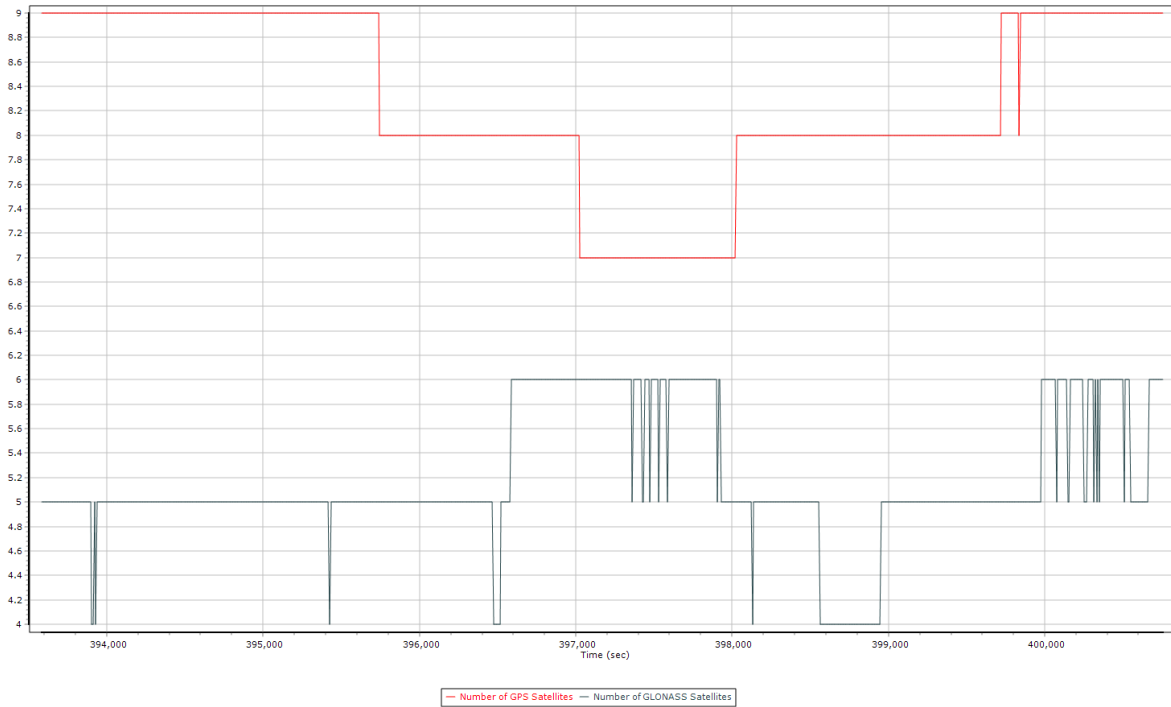
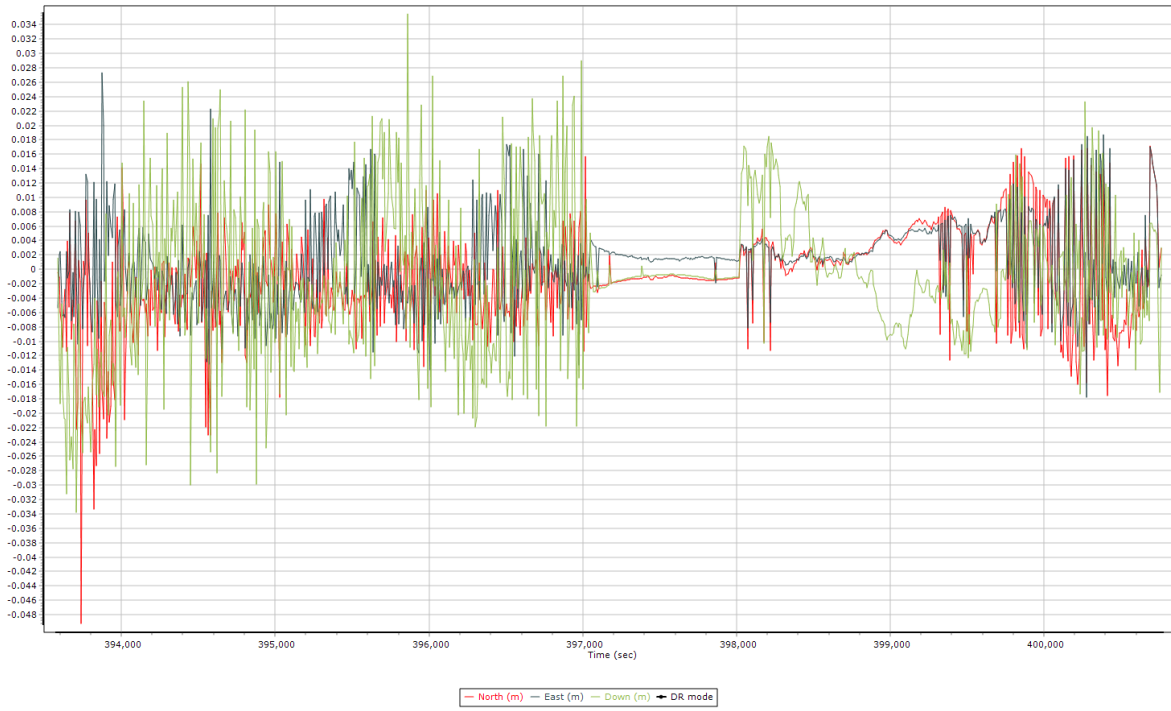
UTC Offset: 18.000

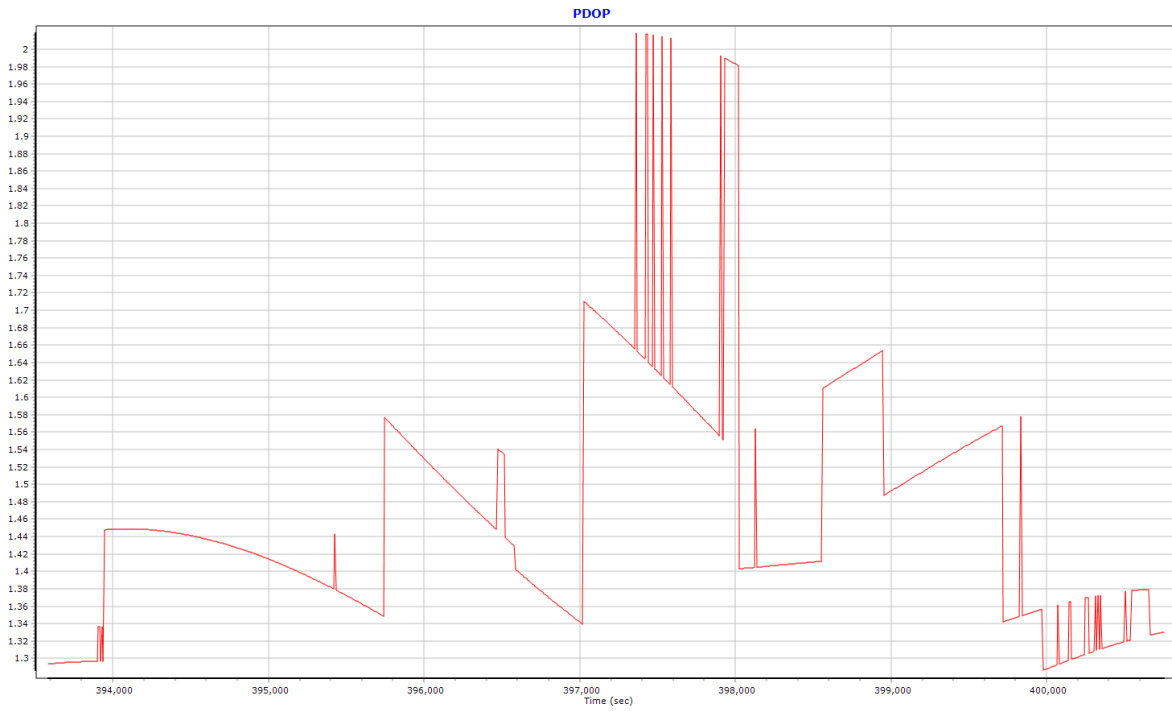
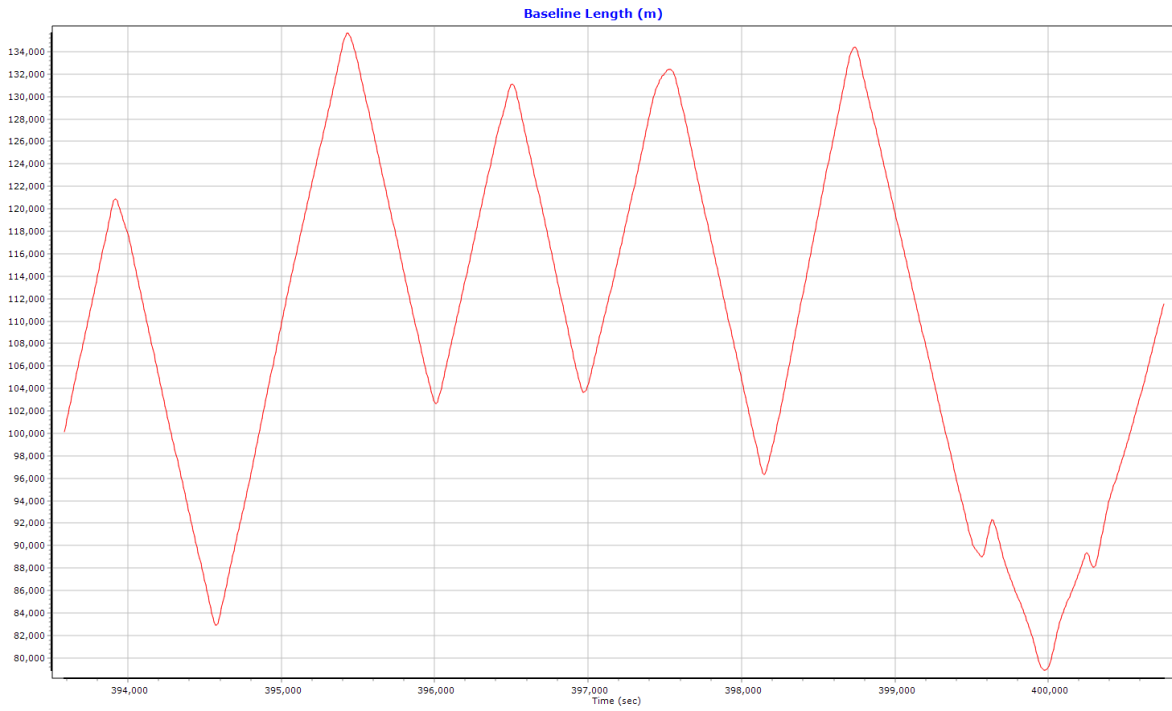
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel



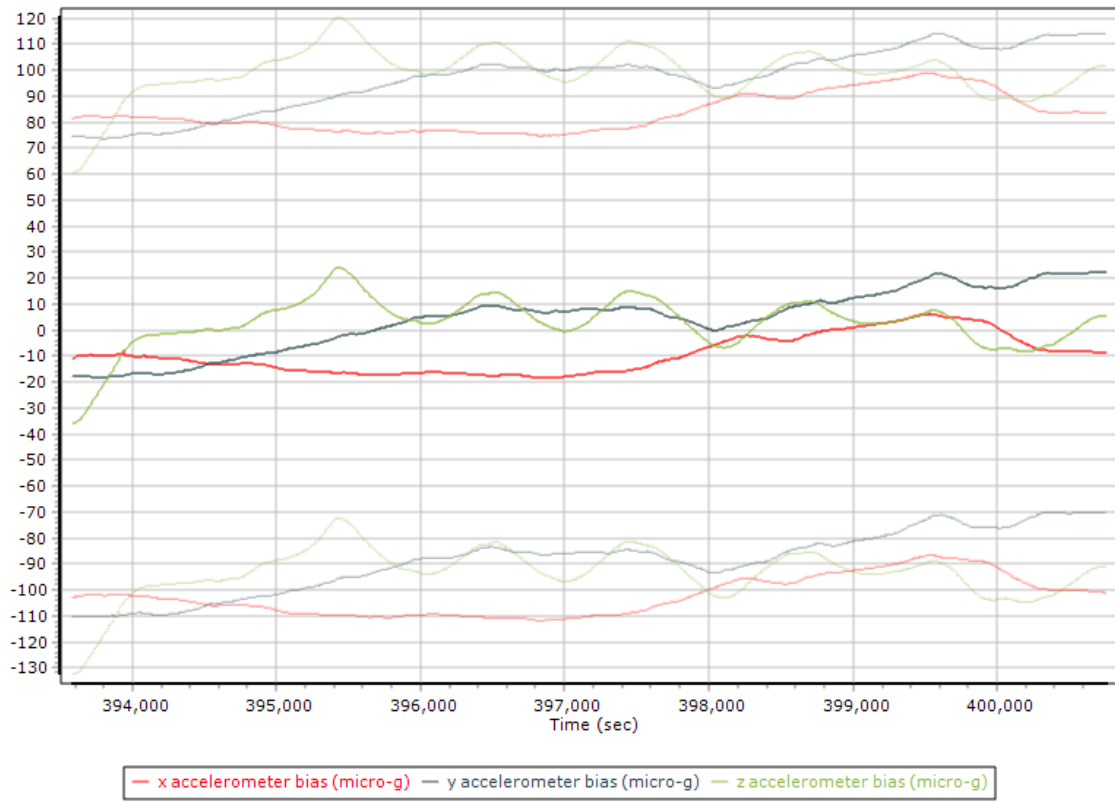


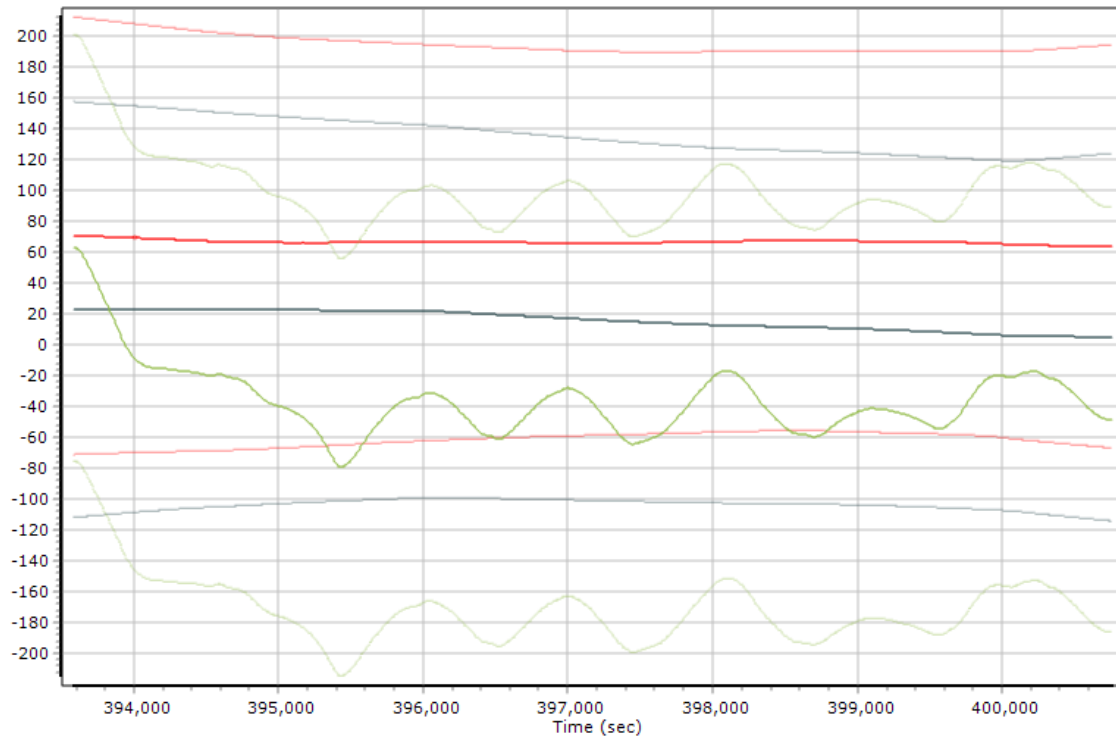




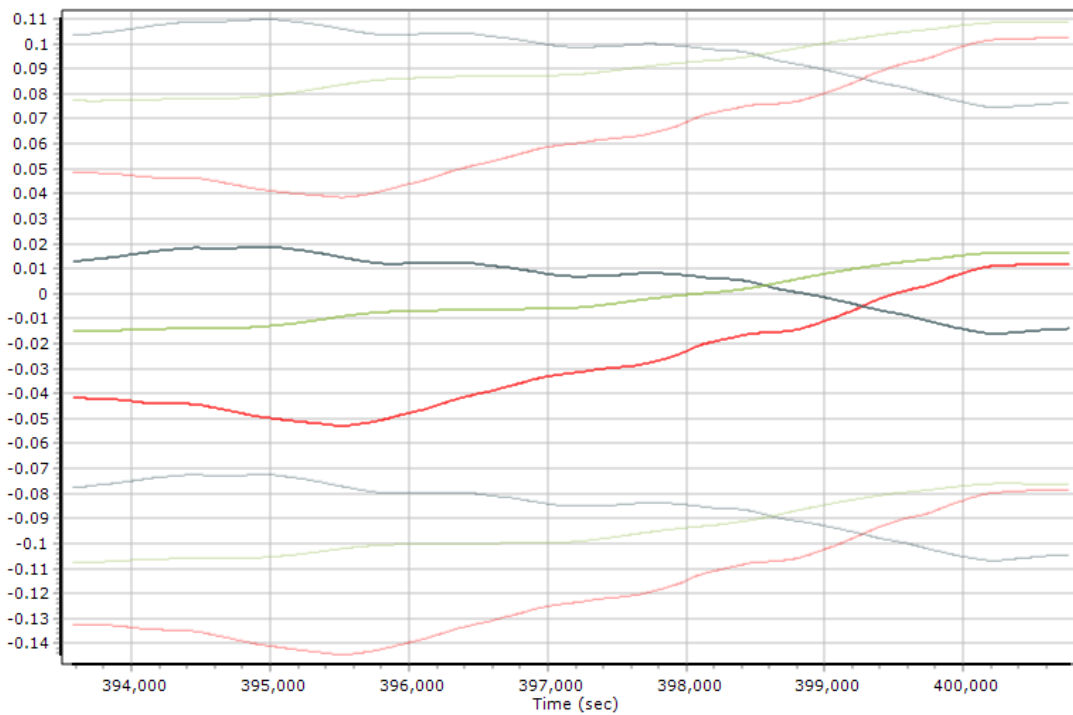


Sensor Errors

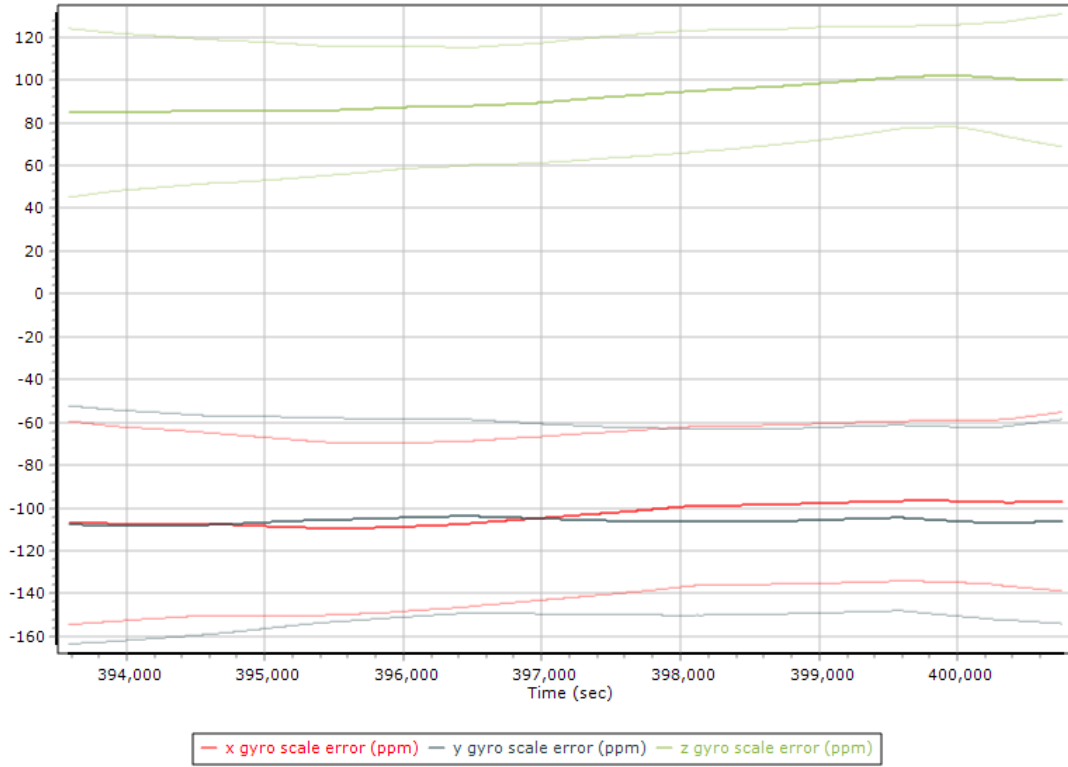




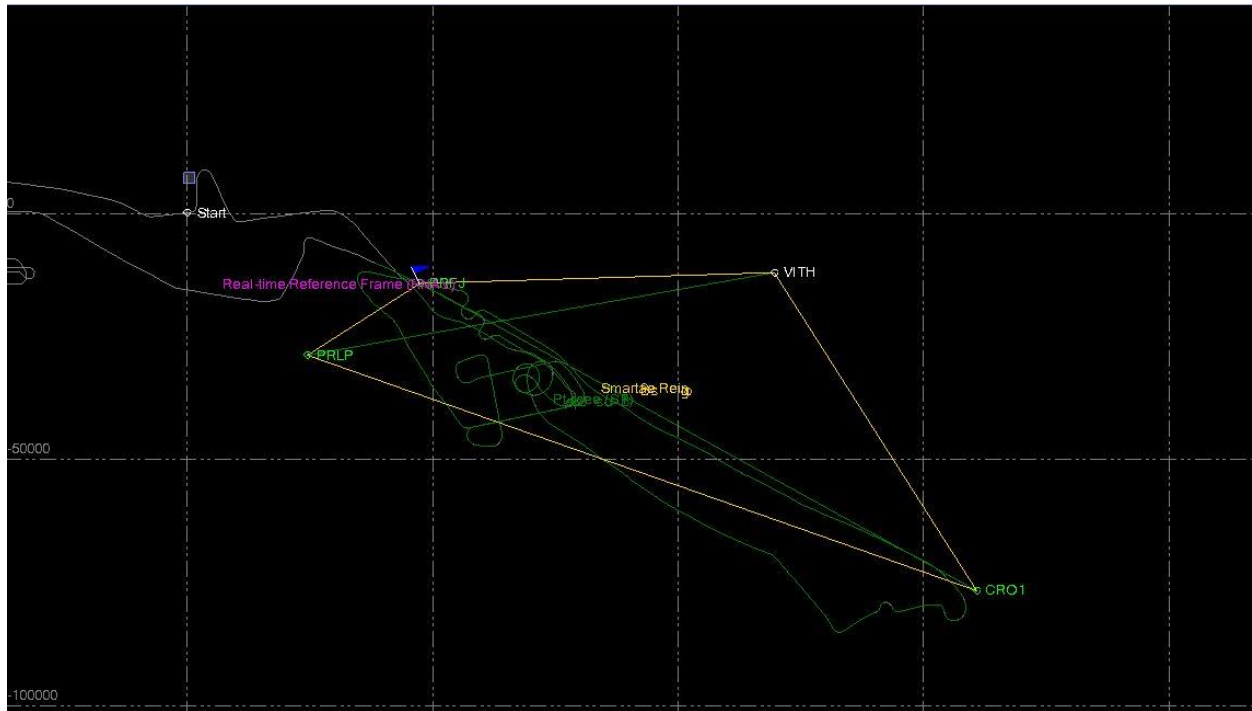
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

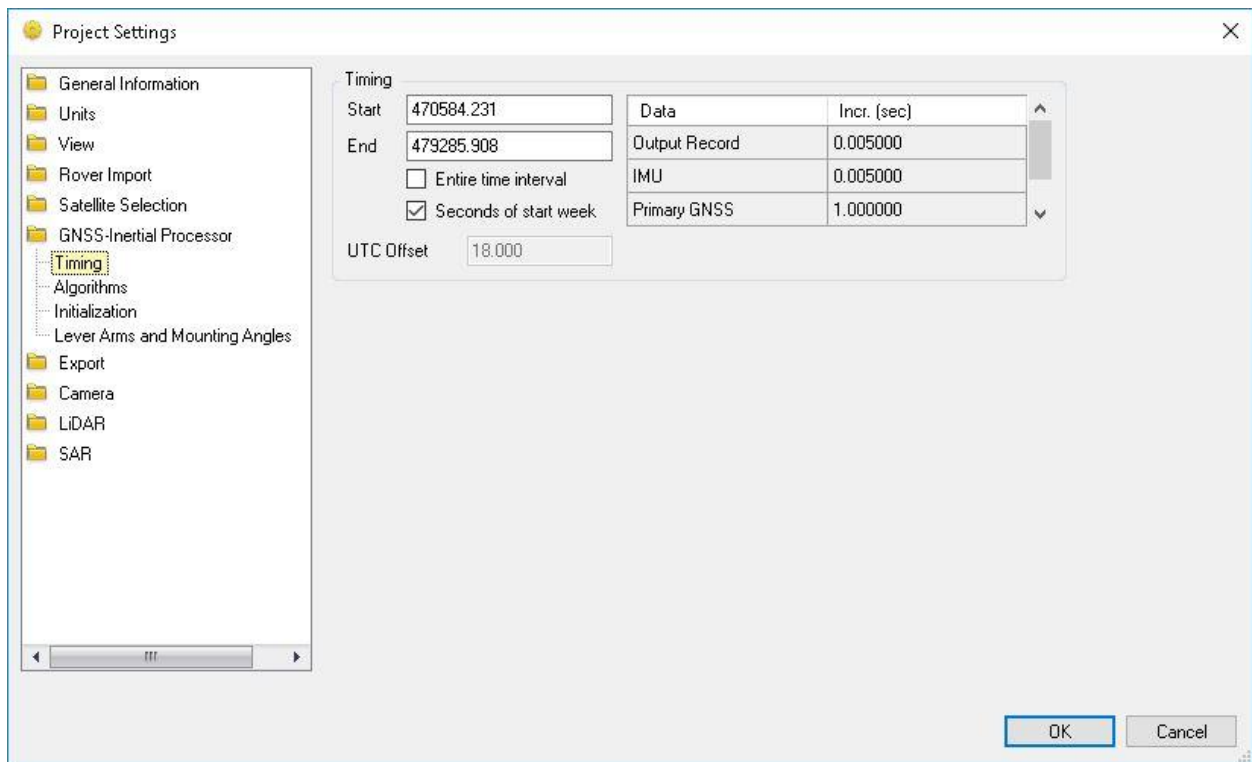
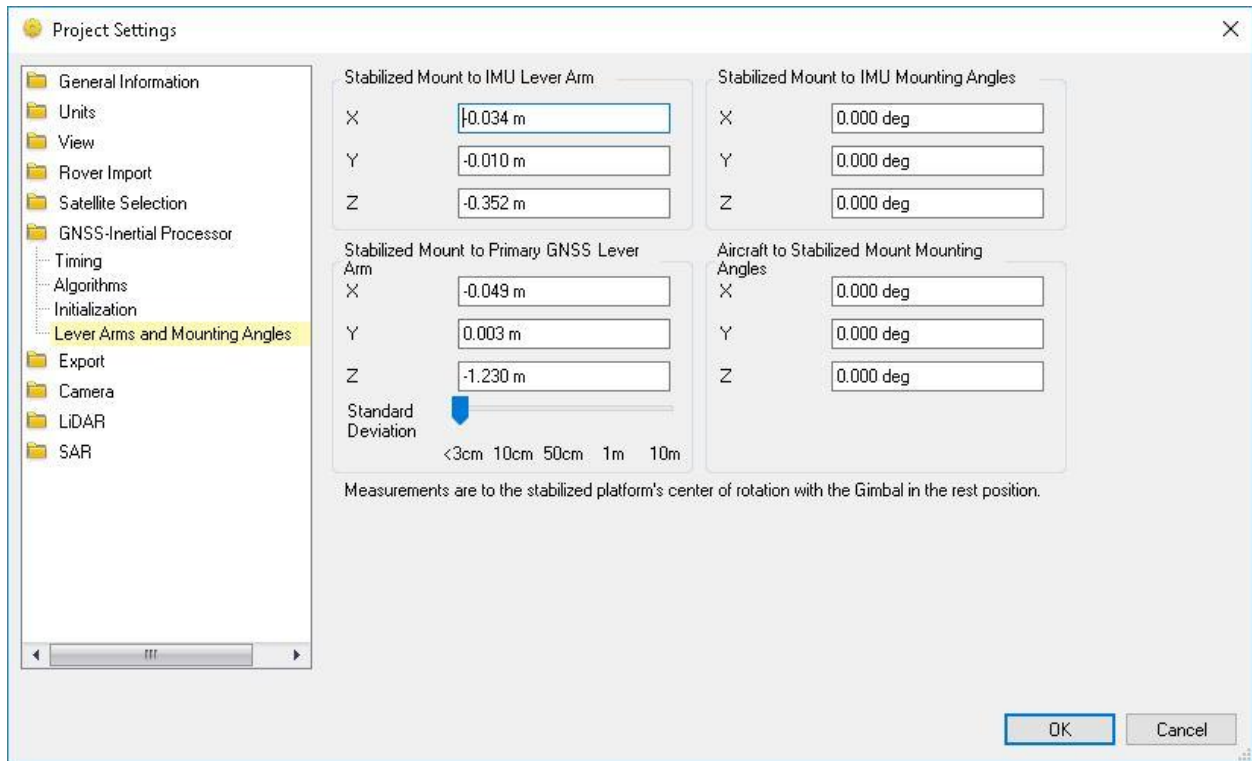


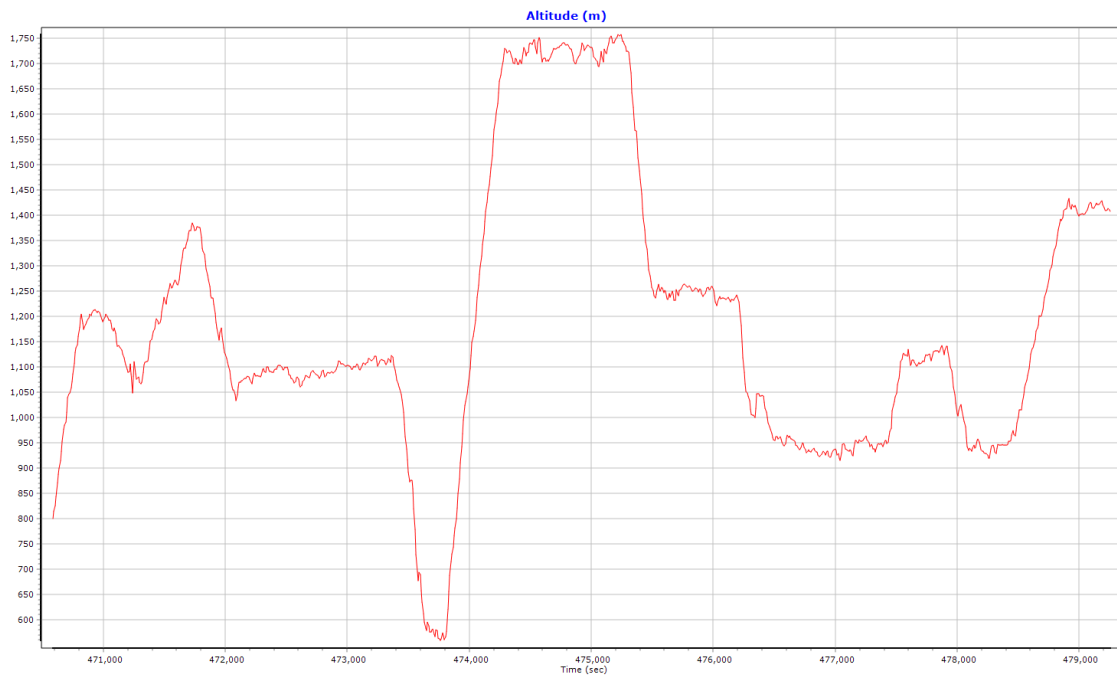
— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

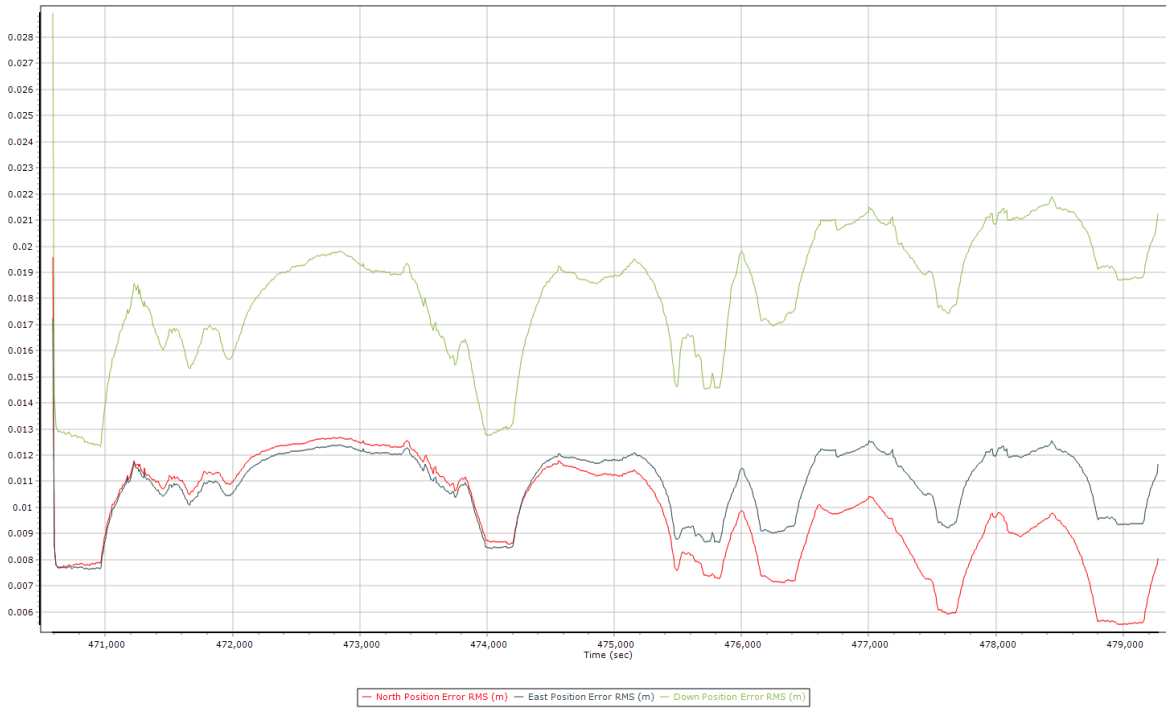


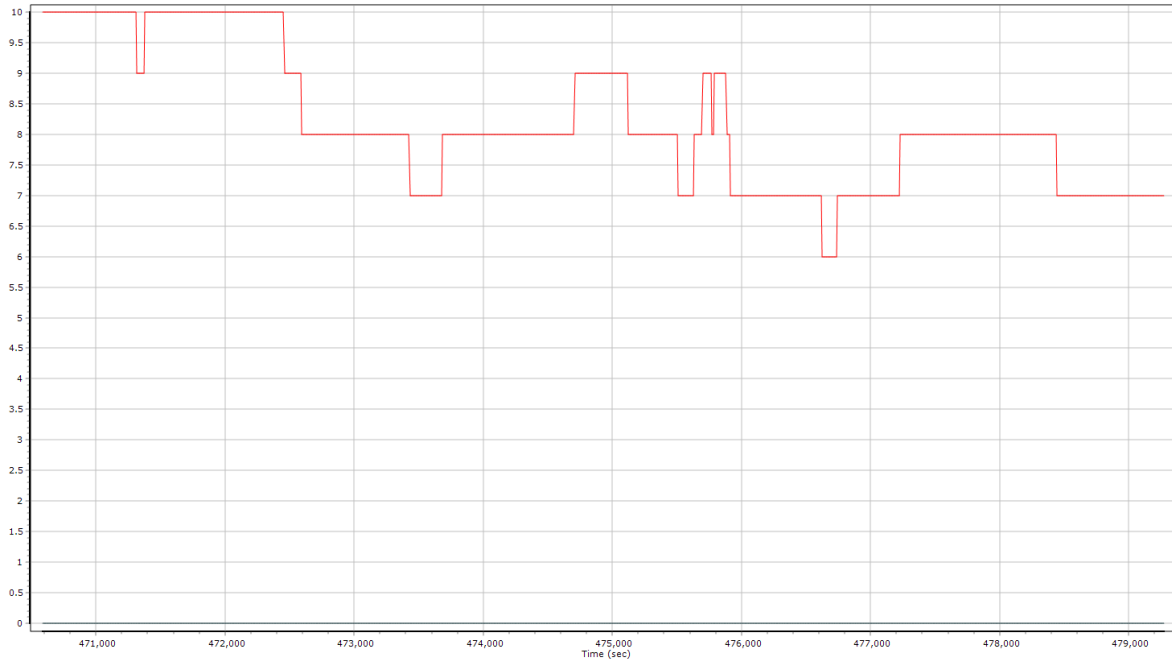
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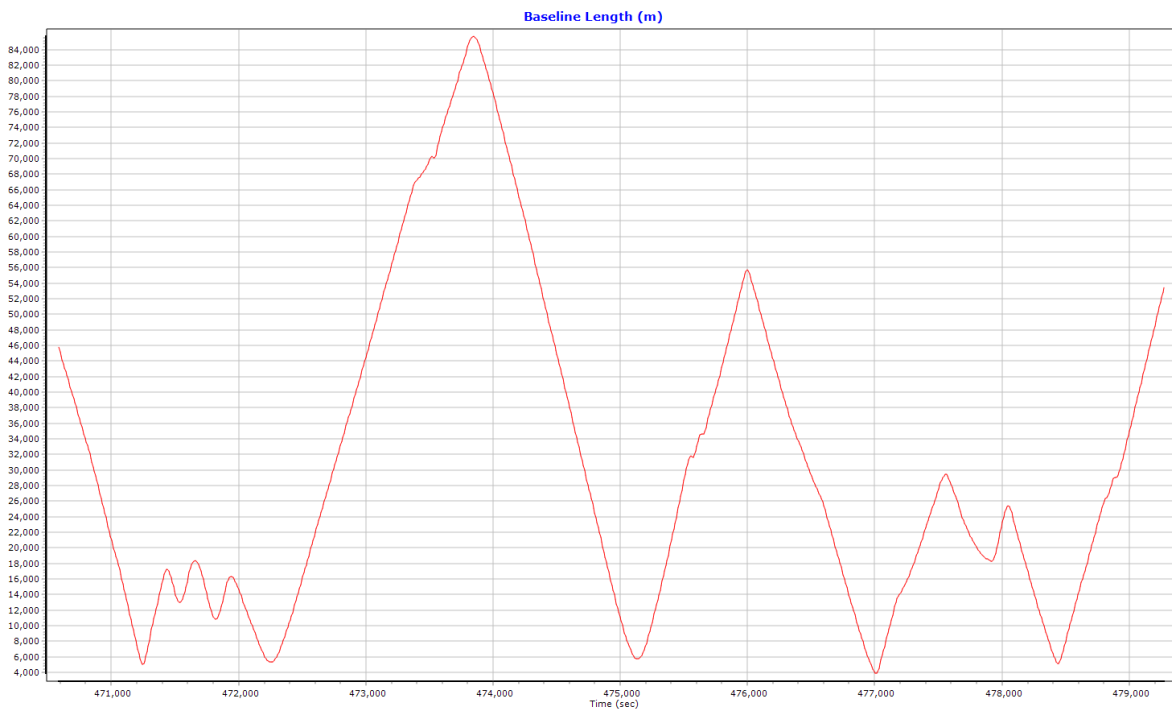


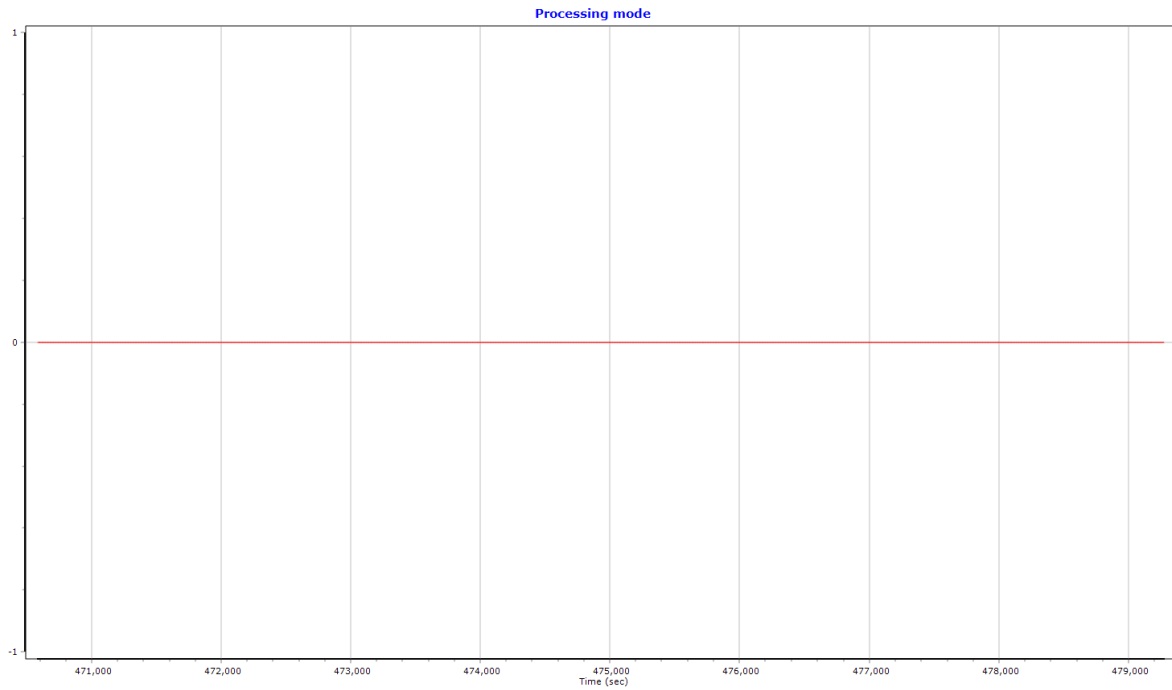
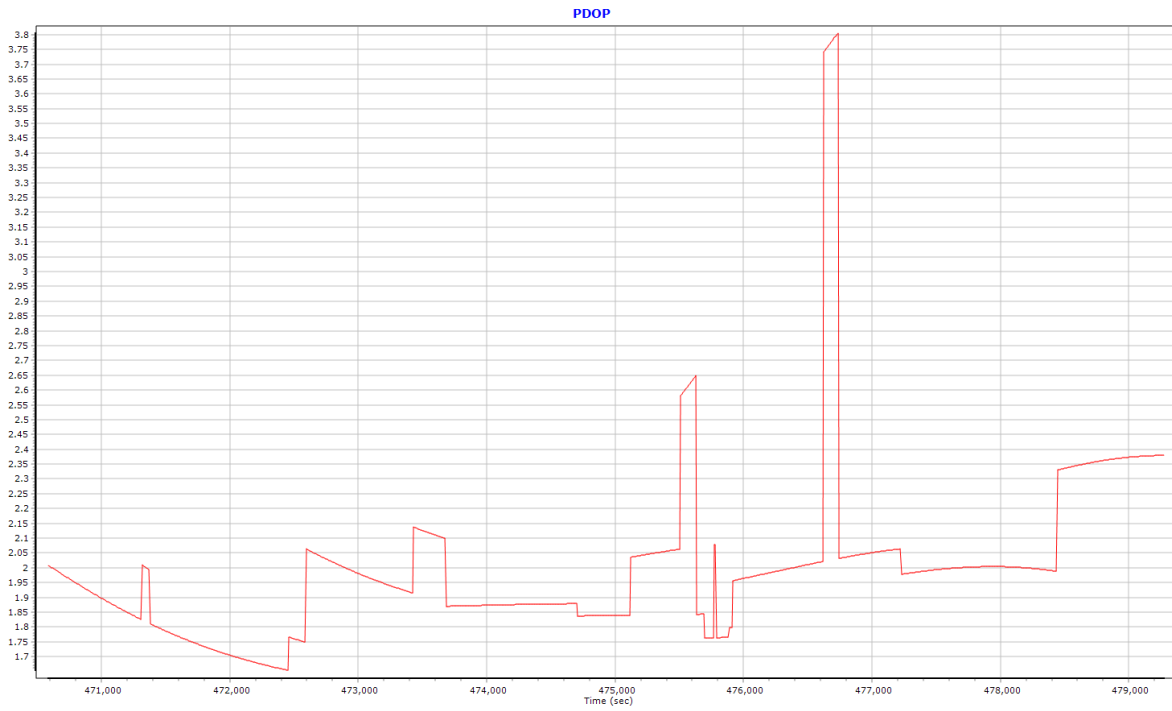




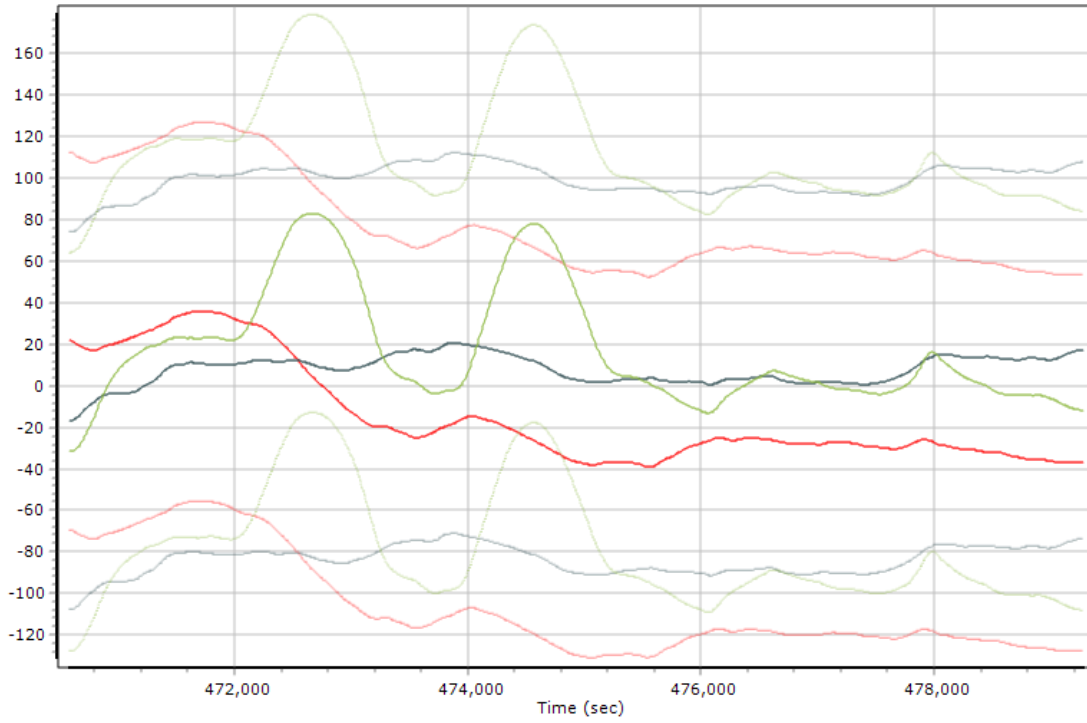


— Number of GPS Satellites — Number of GLONASS Satellites

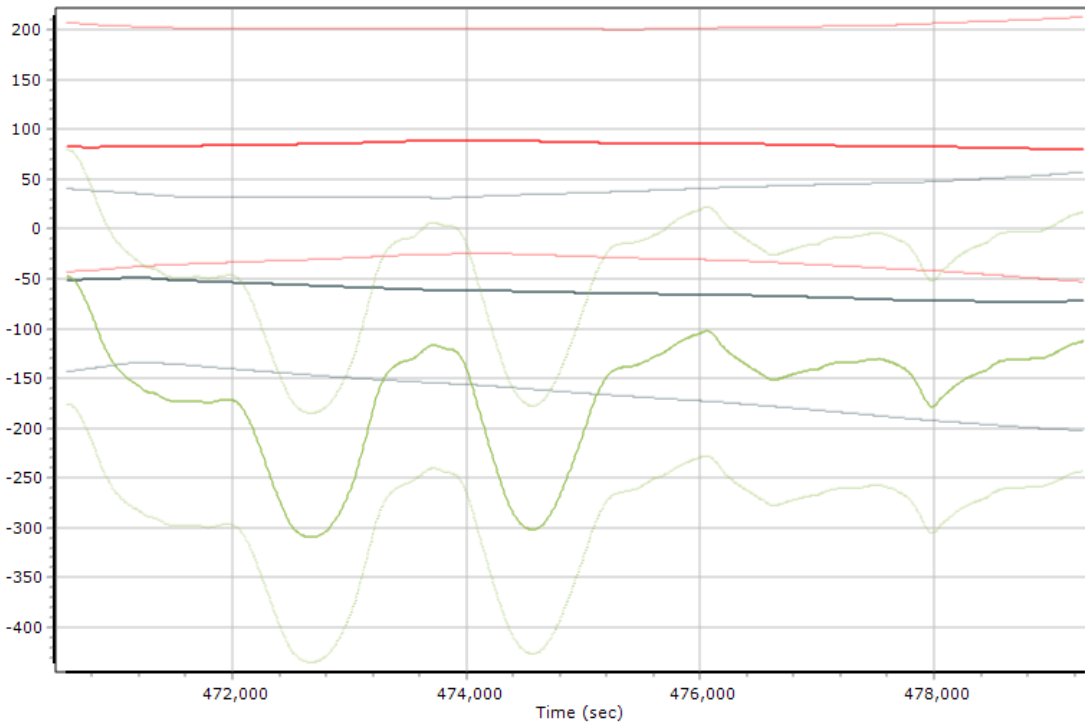




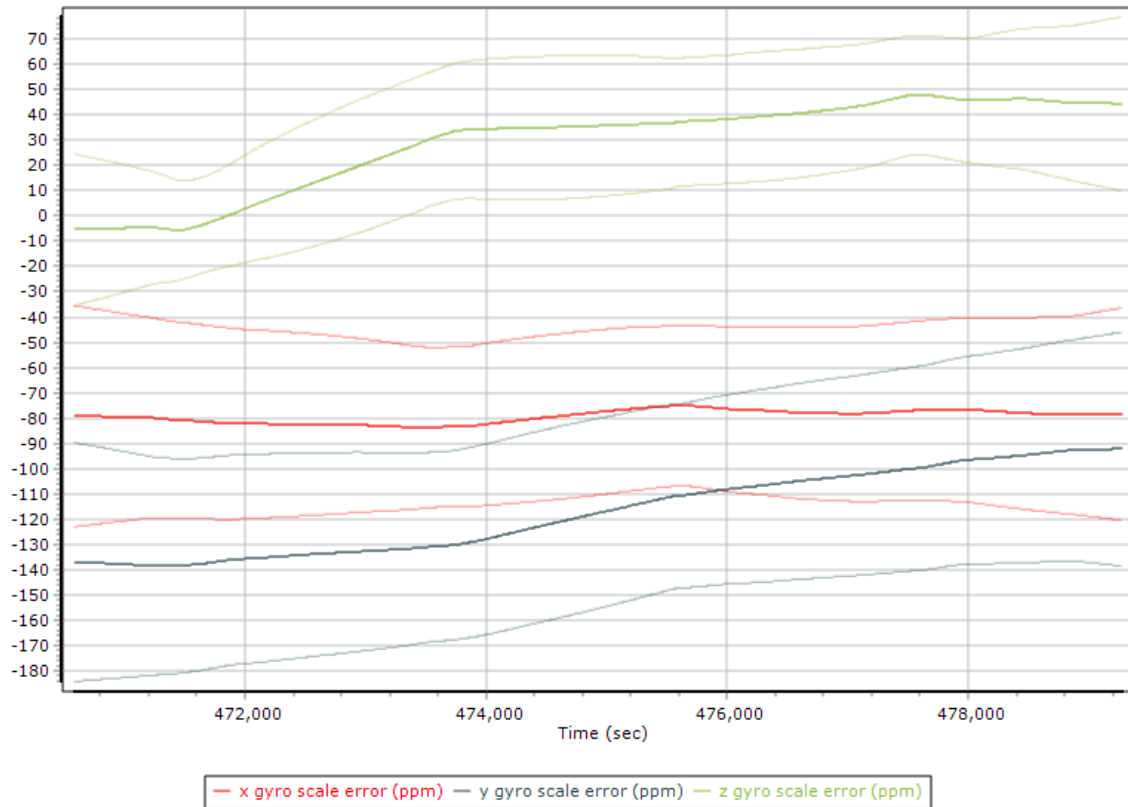
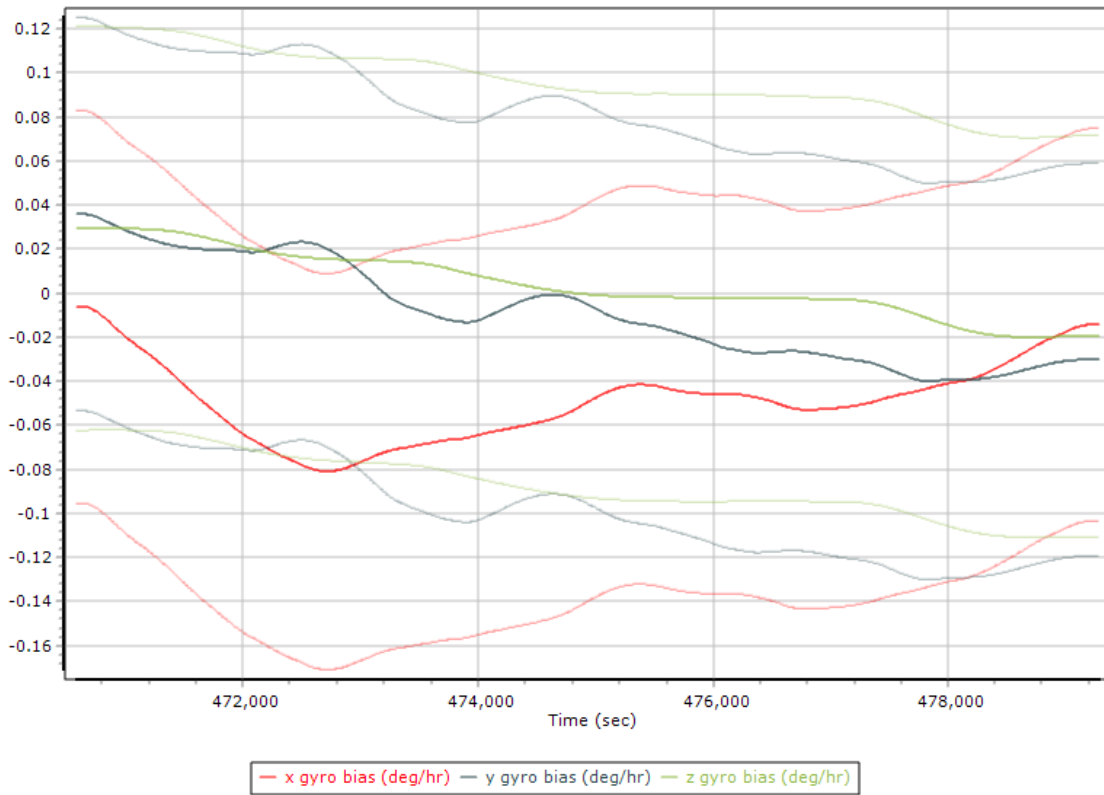
Sensor Errors



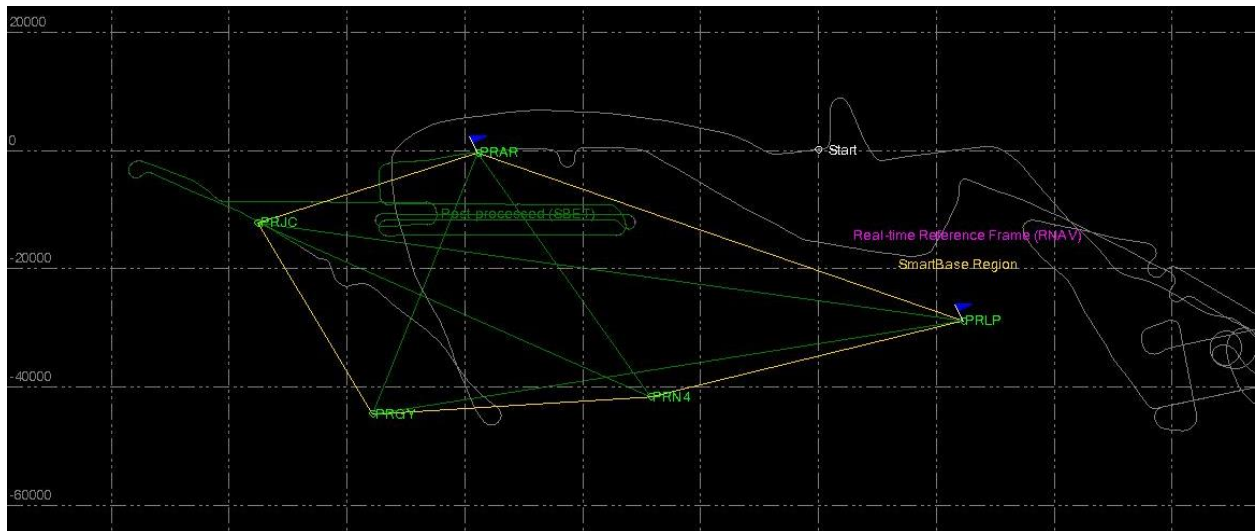
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



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Project Settings

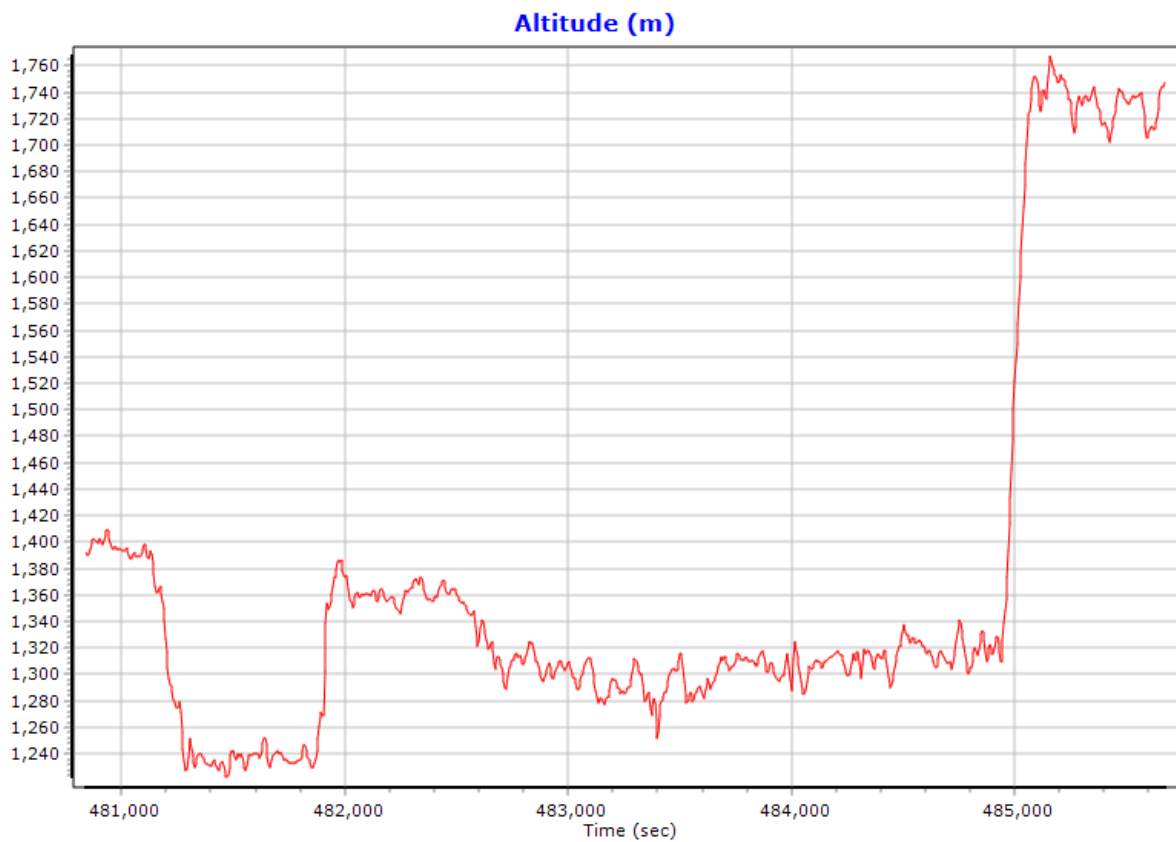
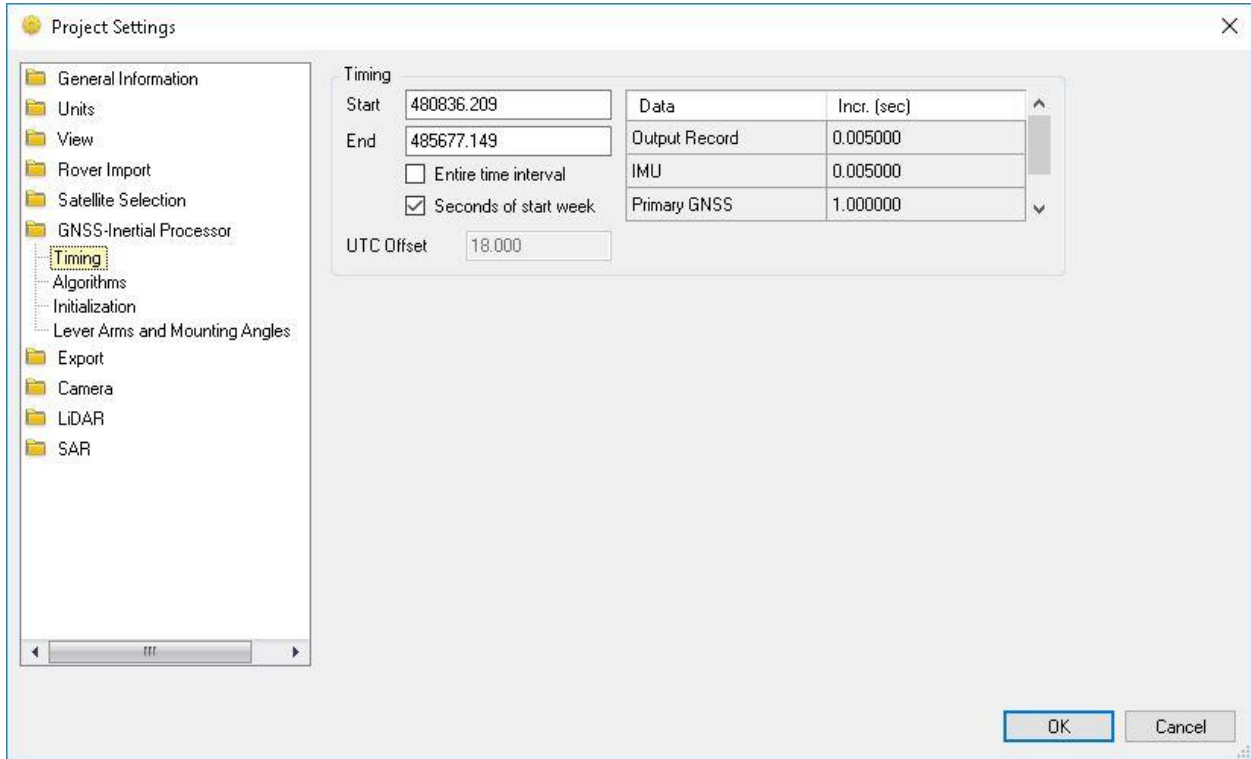
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LIDAR
- SAR

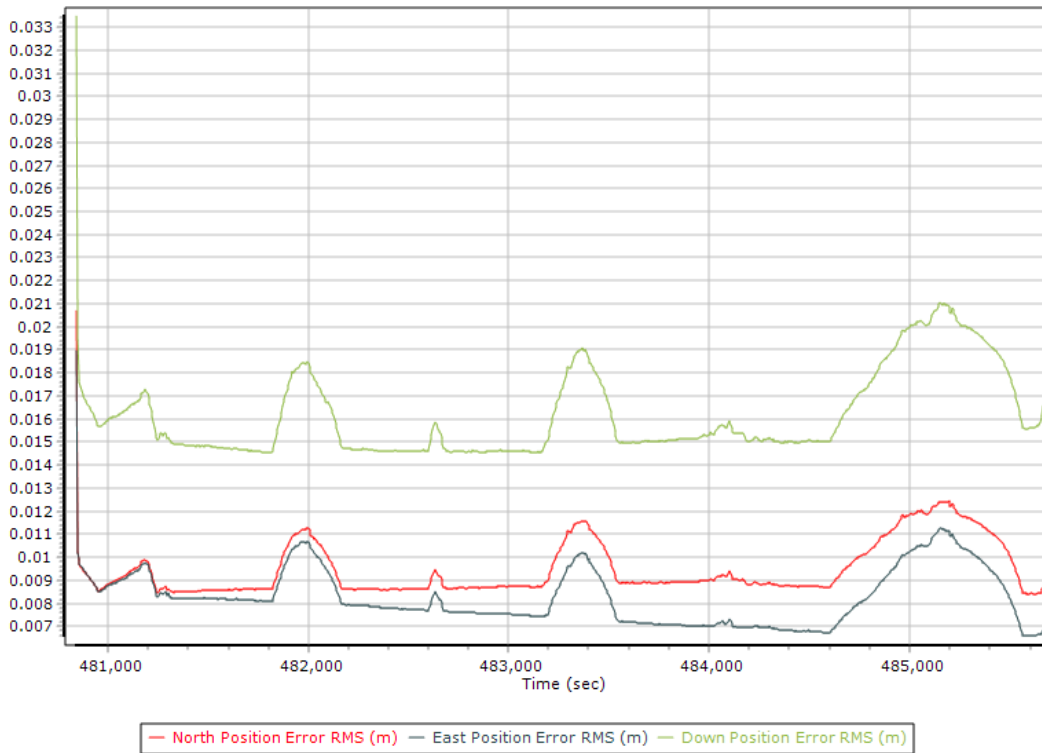
Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.049 m	0.003 m	-1.230 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

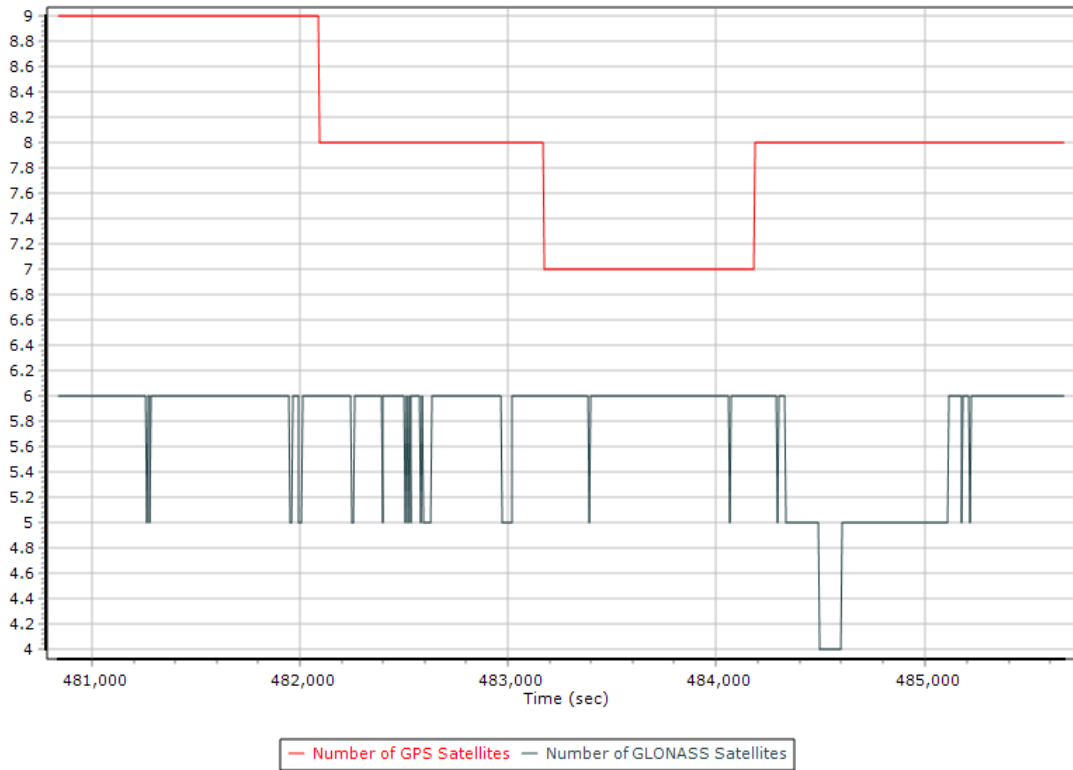
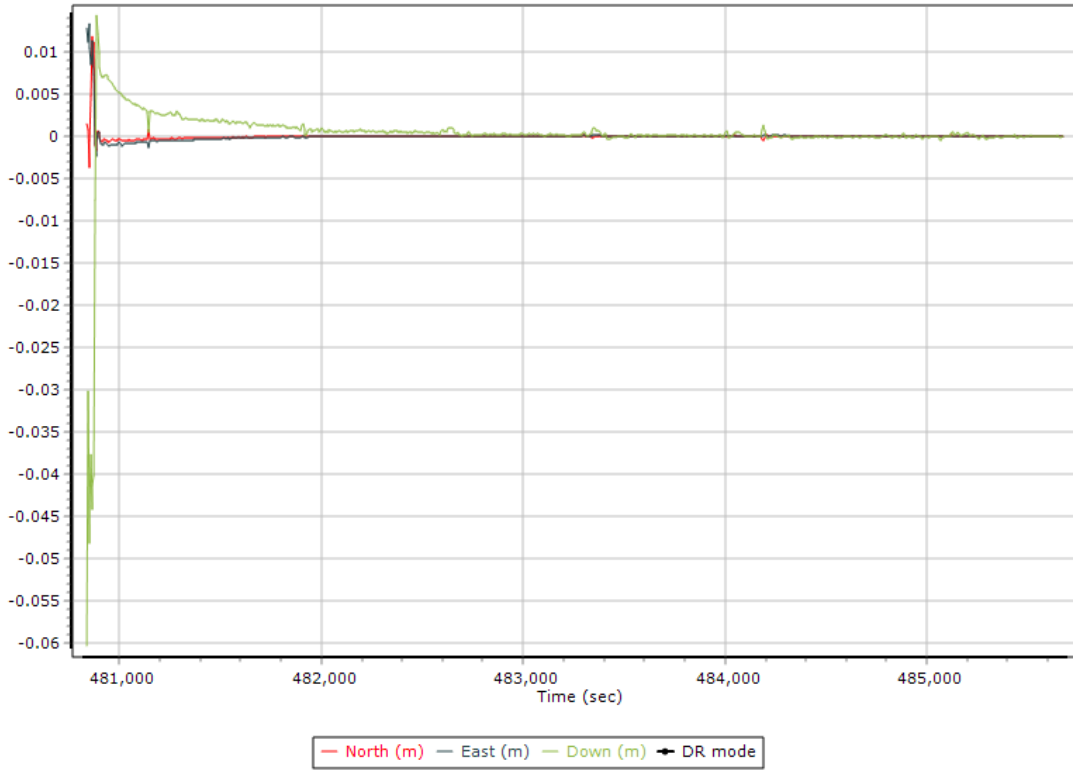
Standard Deviation: <3cm 10cm 50cm 1m 10m

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

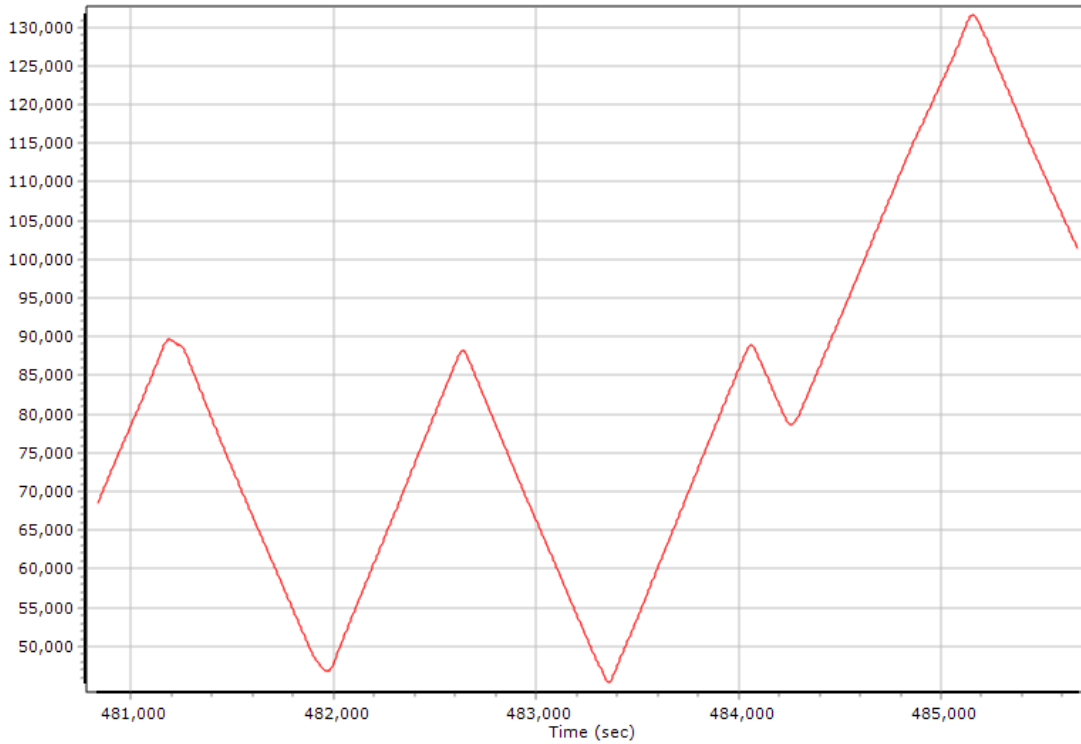
OK Cancel



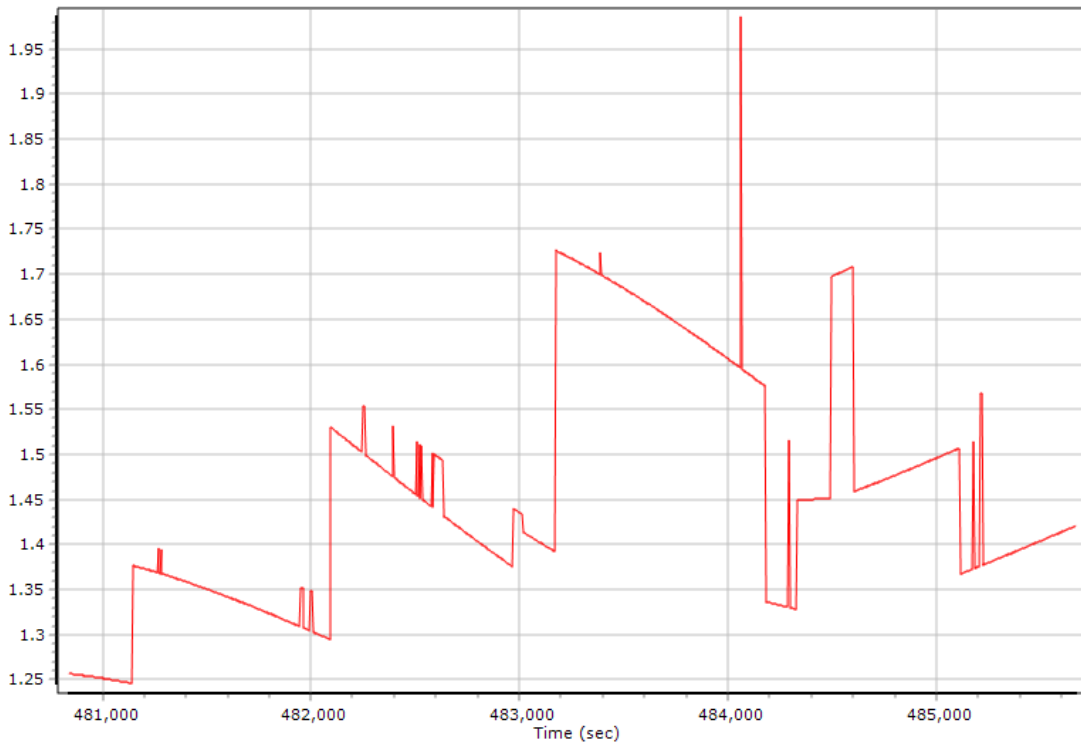




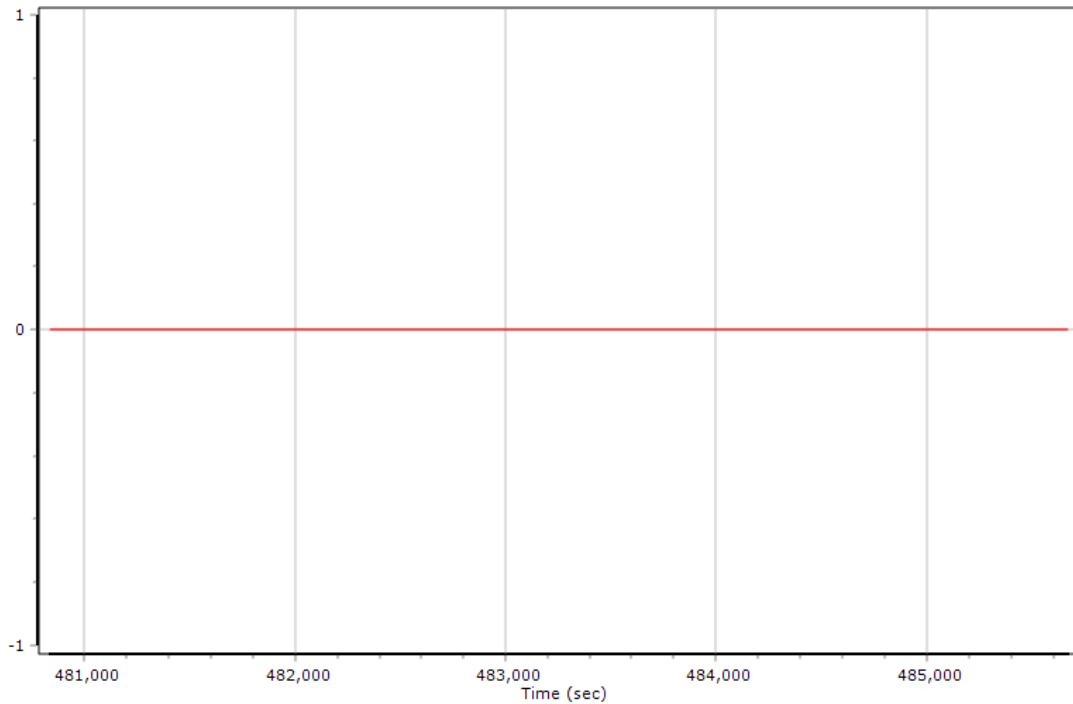
Baseline Length (m)



PDOP

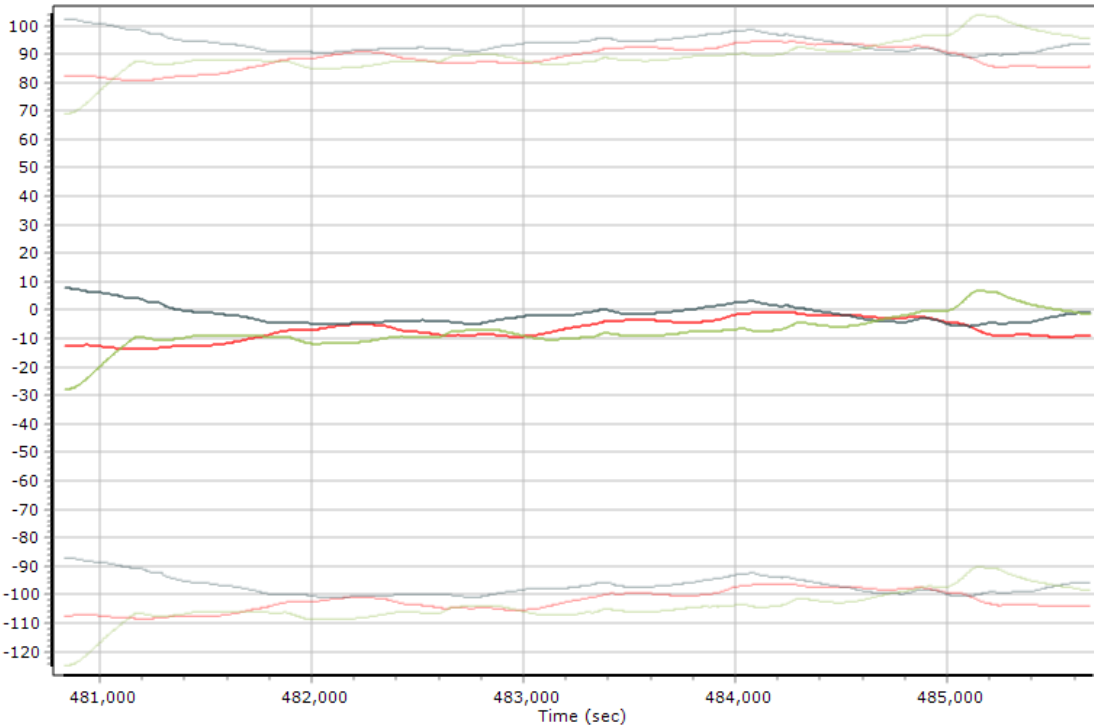


Processing mode

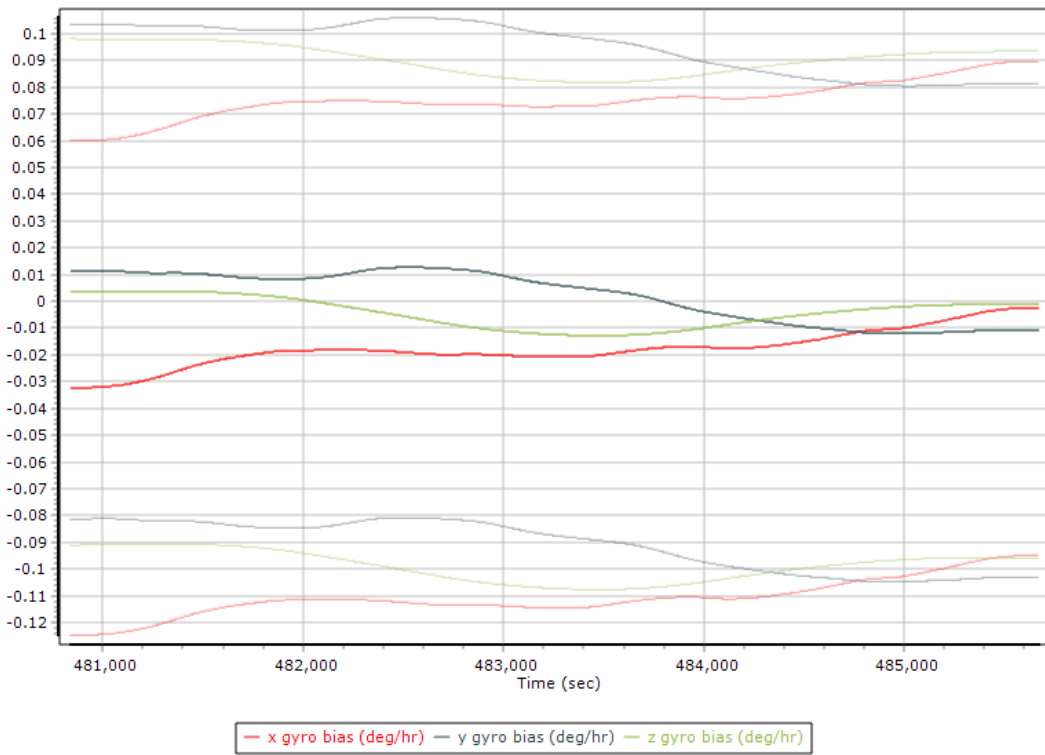
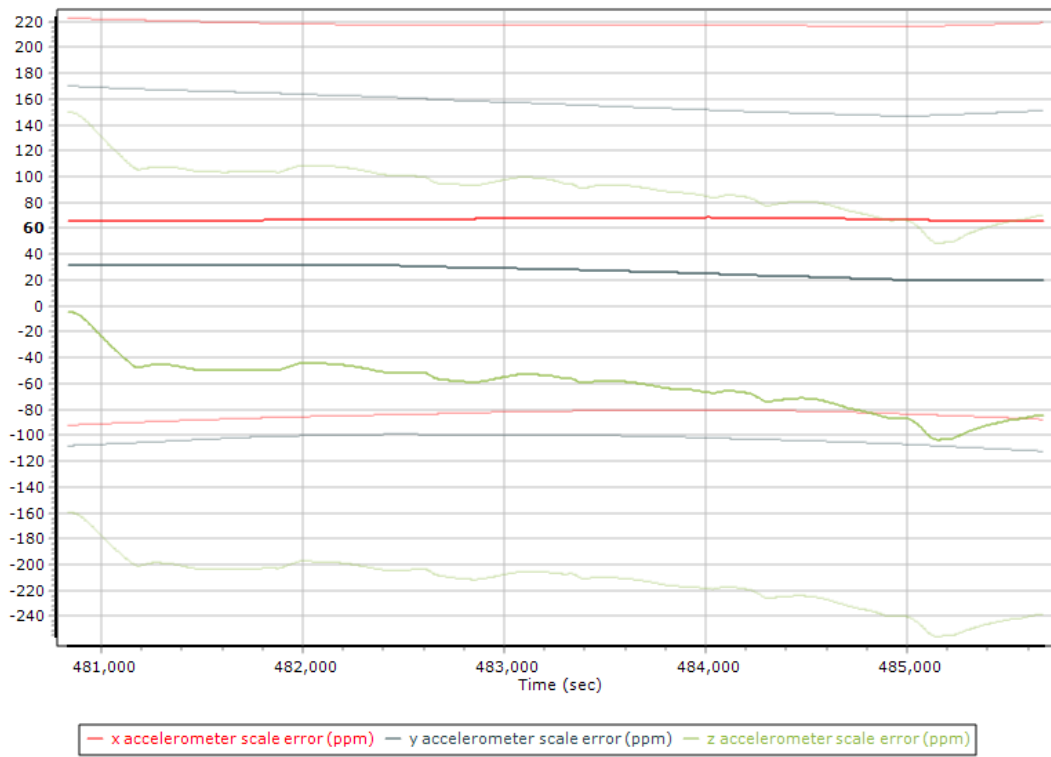


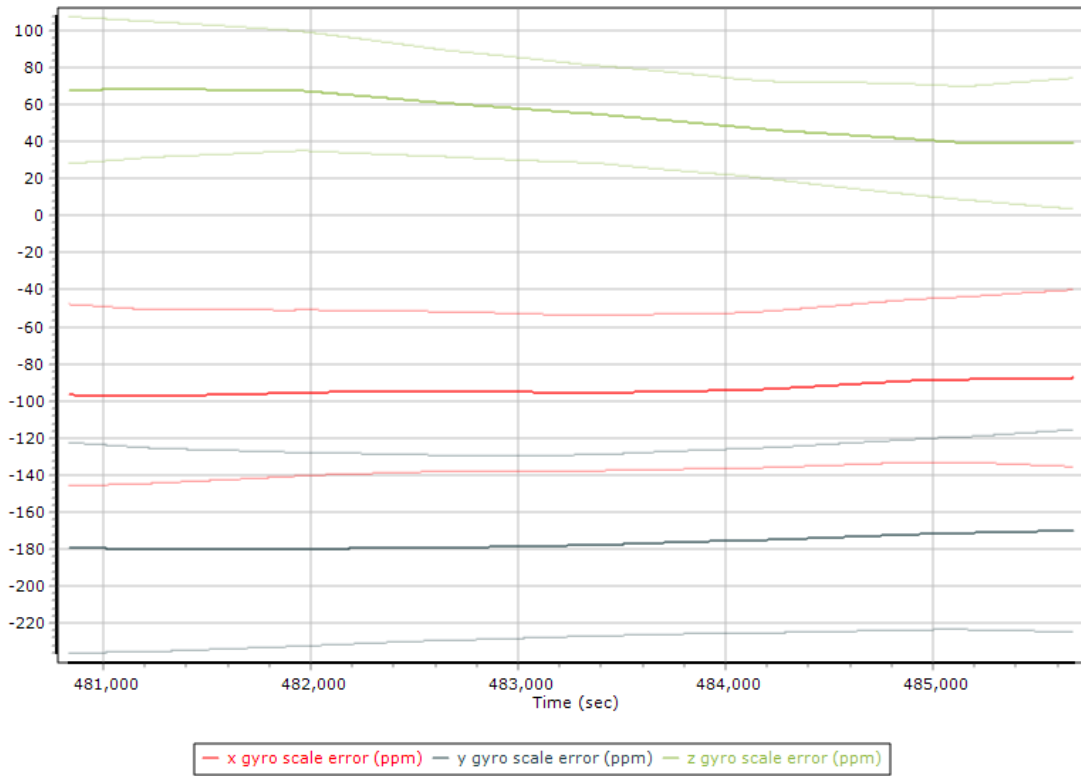
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

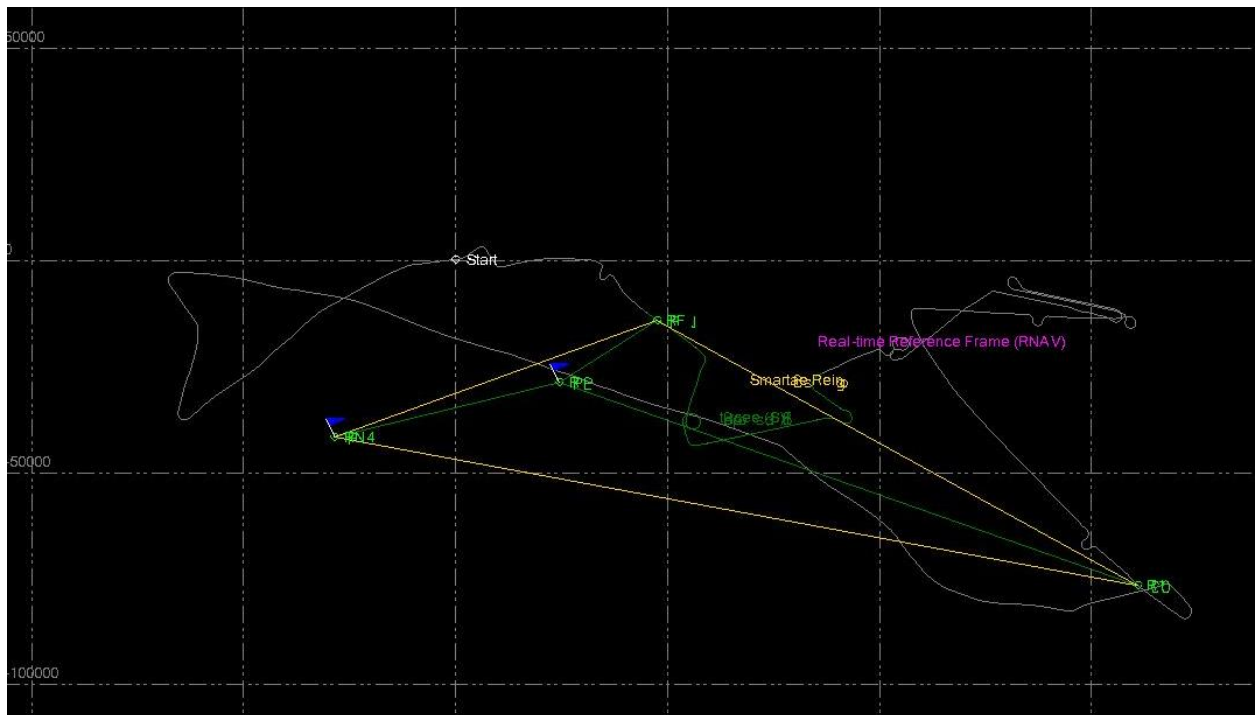


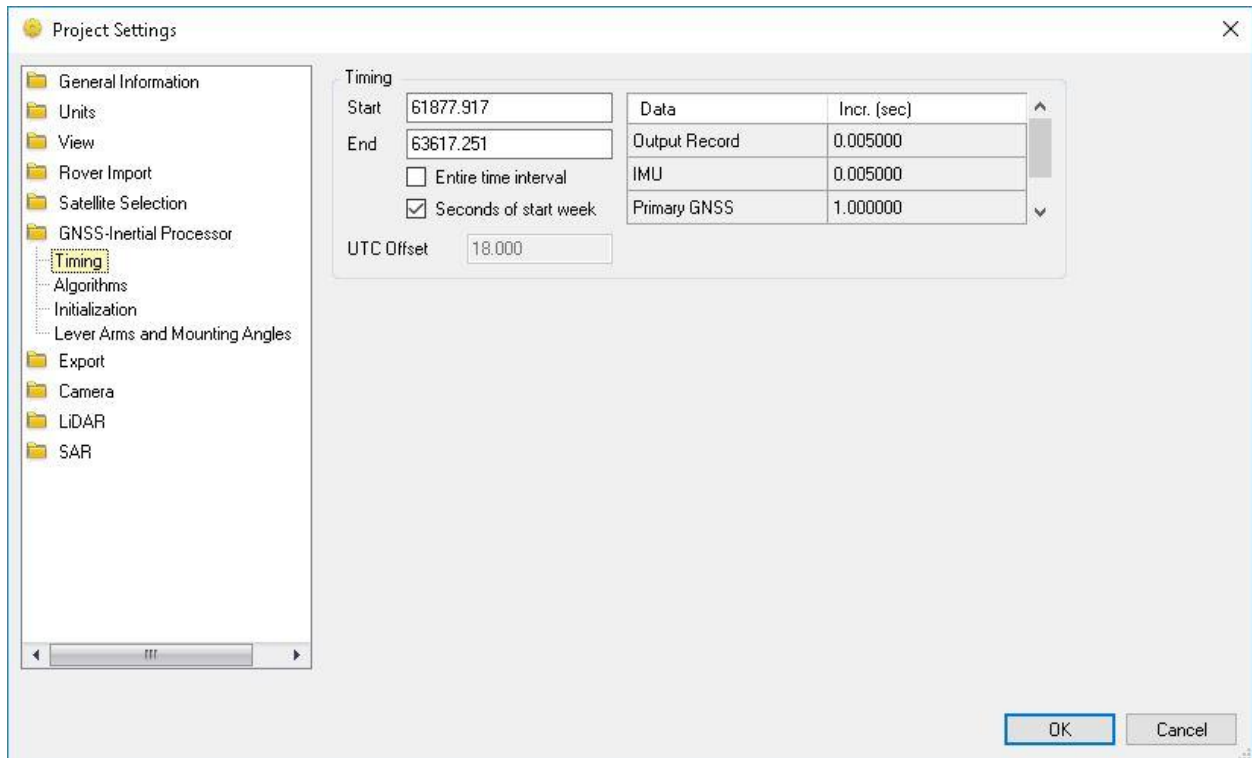
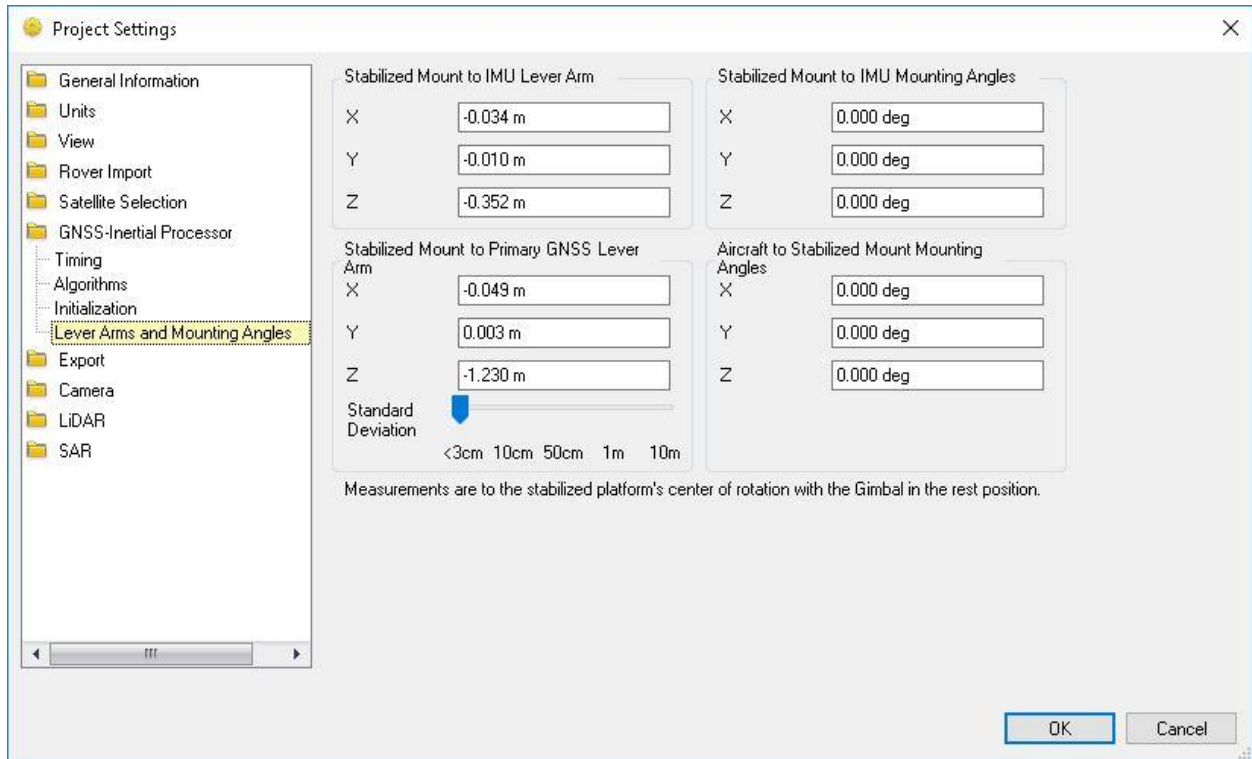
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)

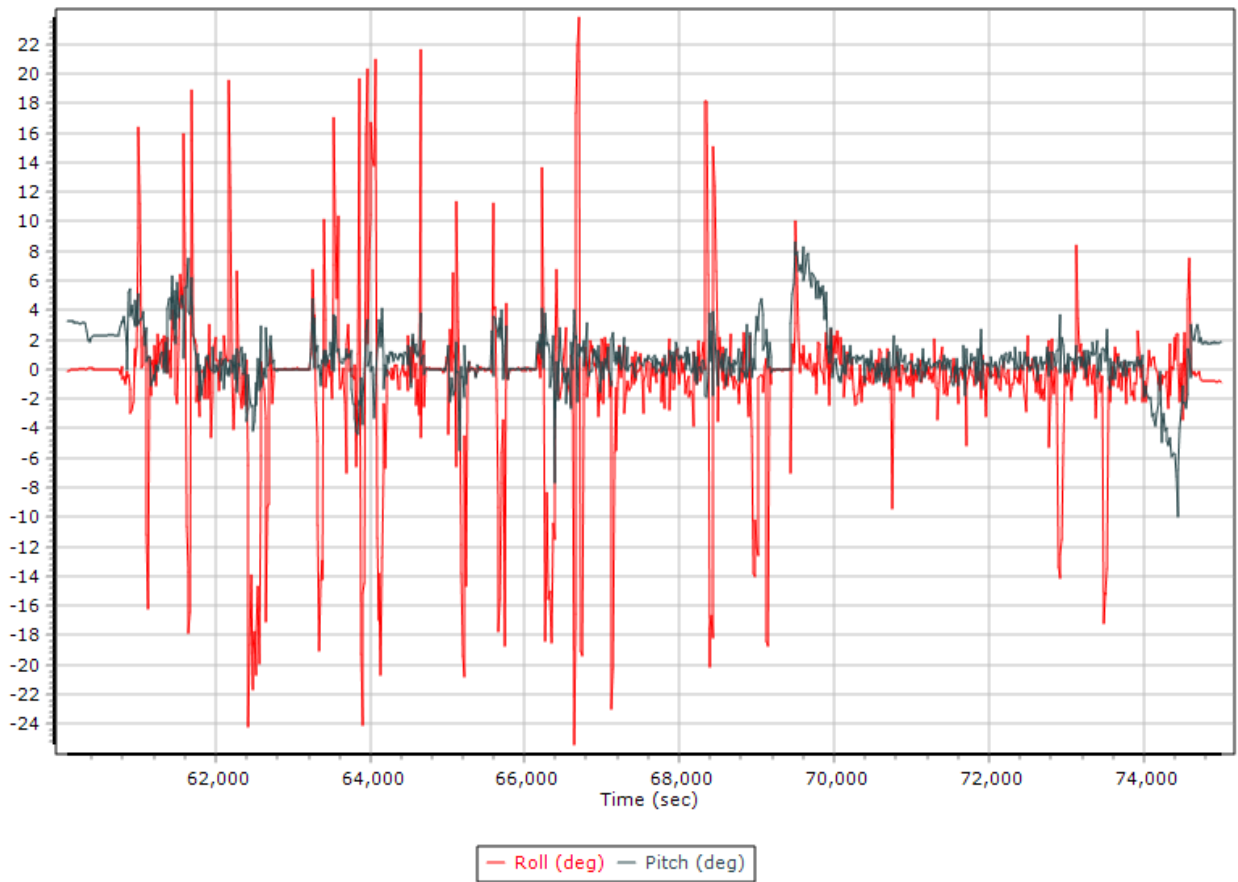
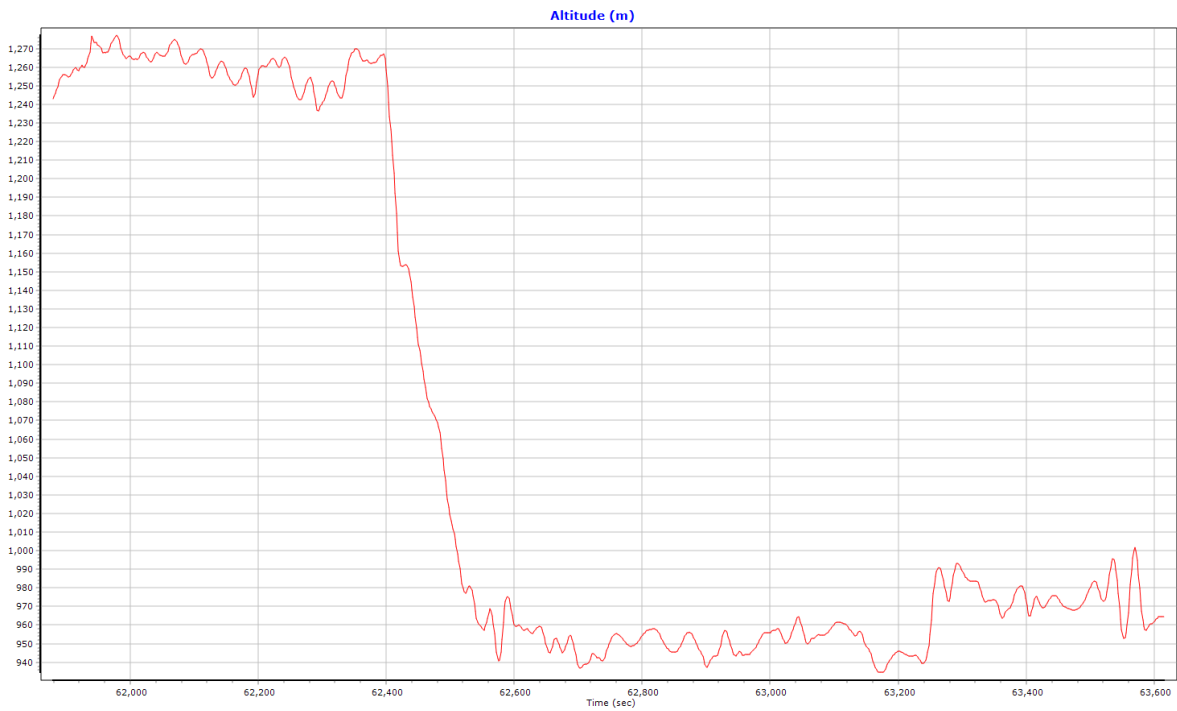


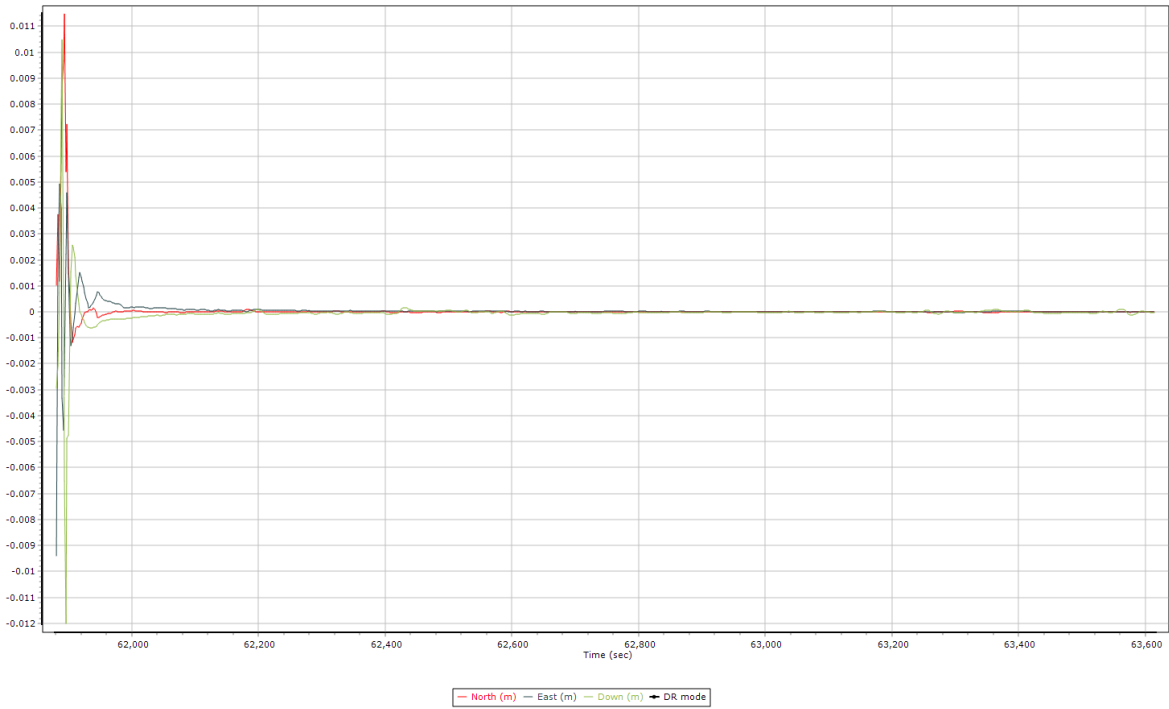
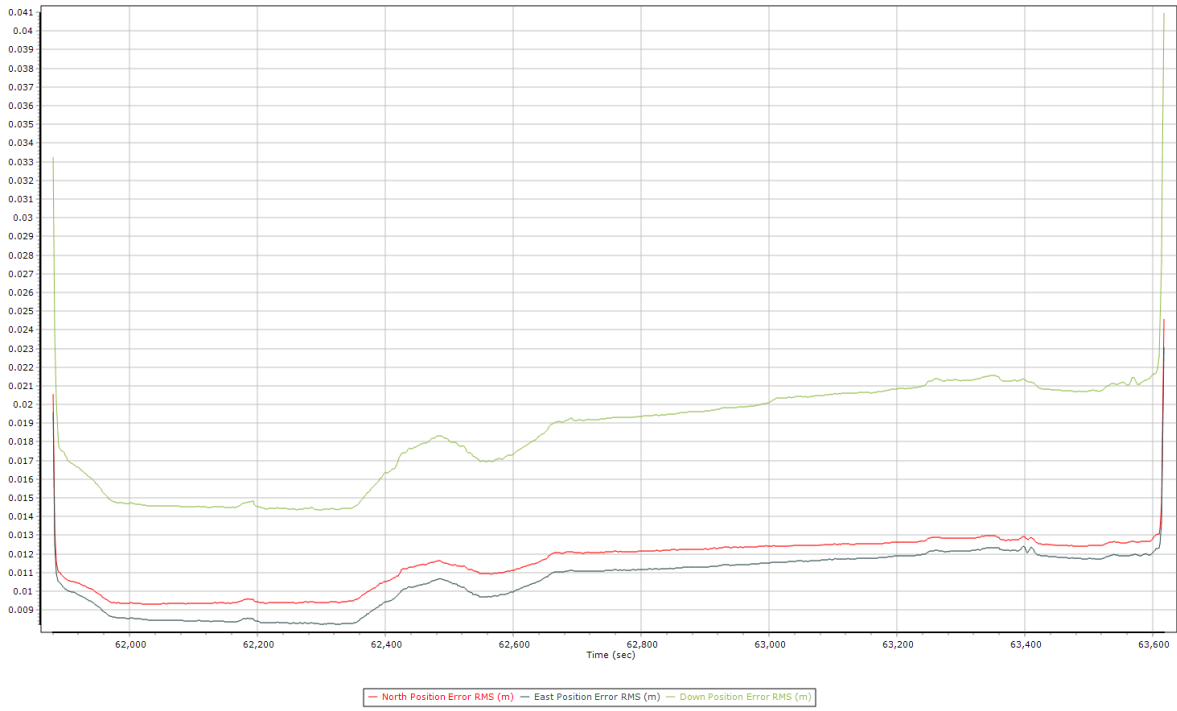


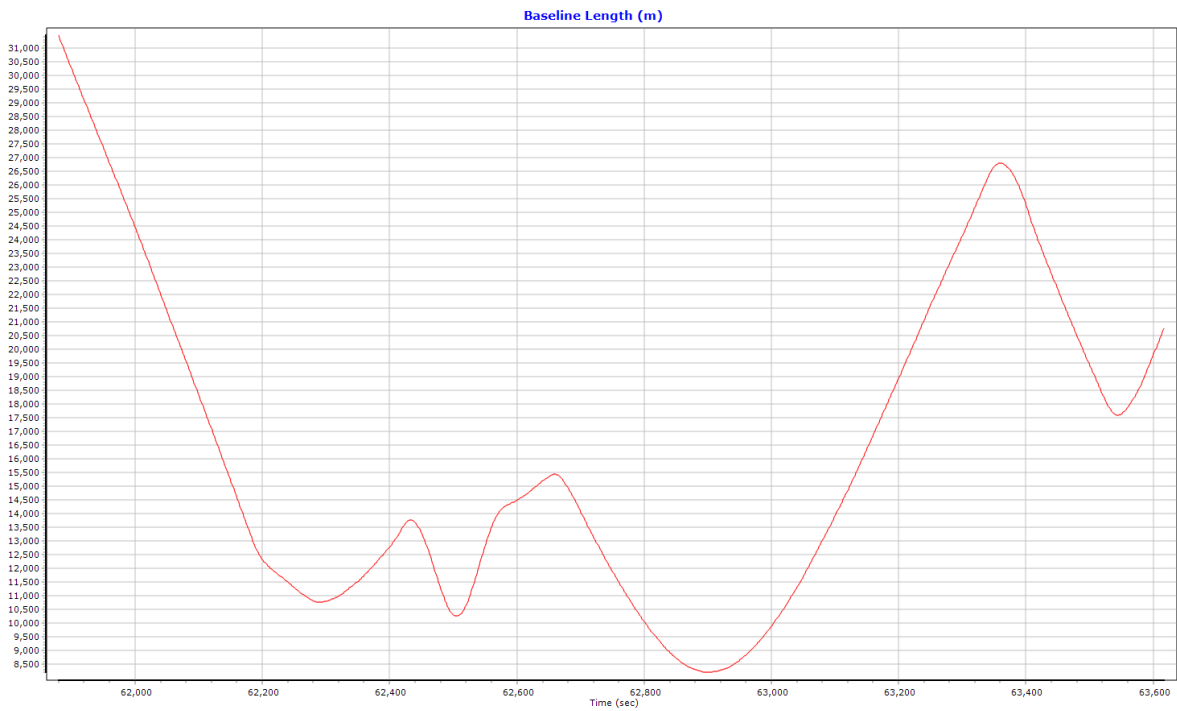
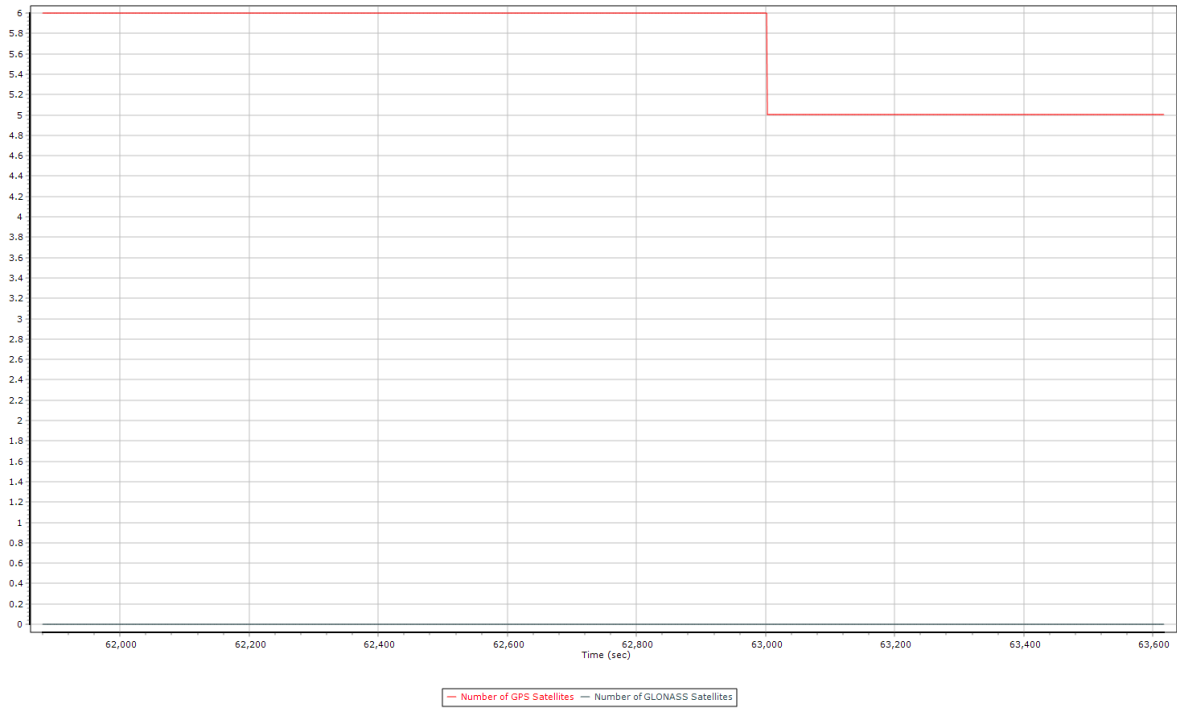
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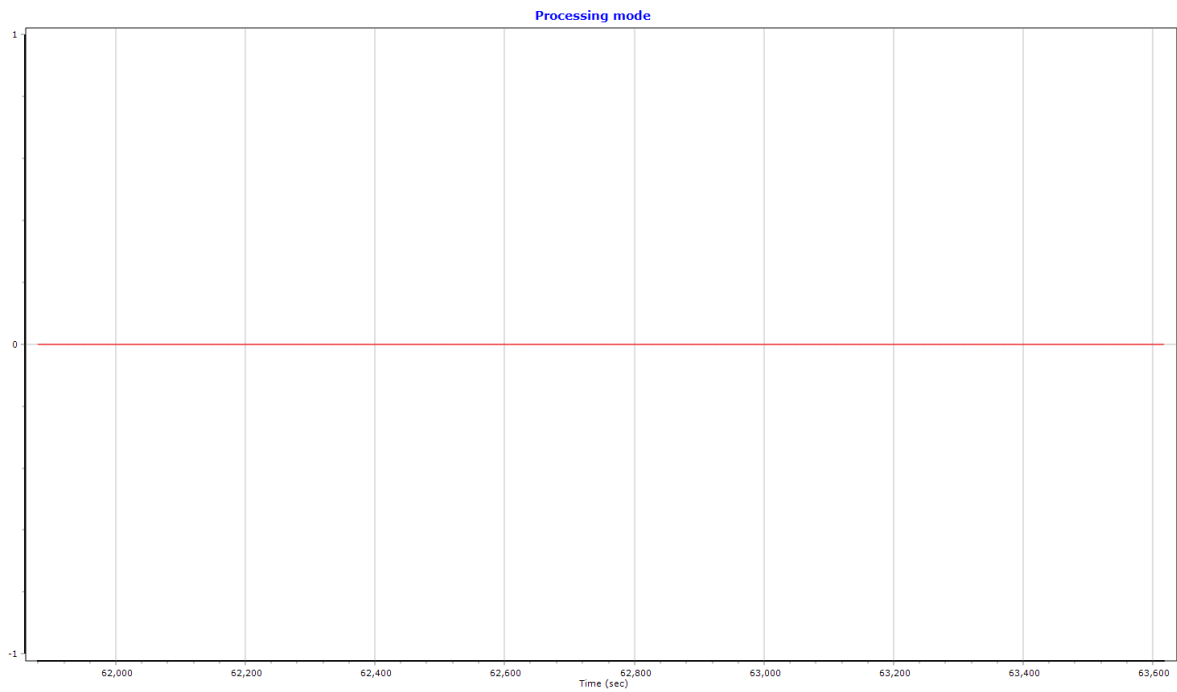
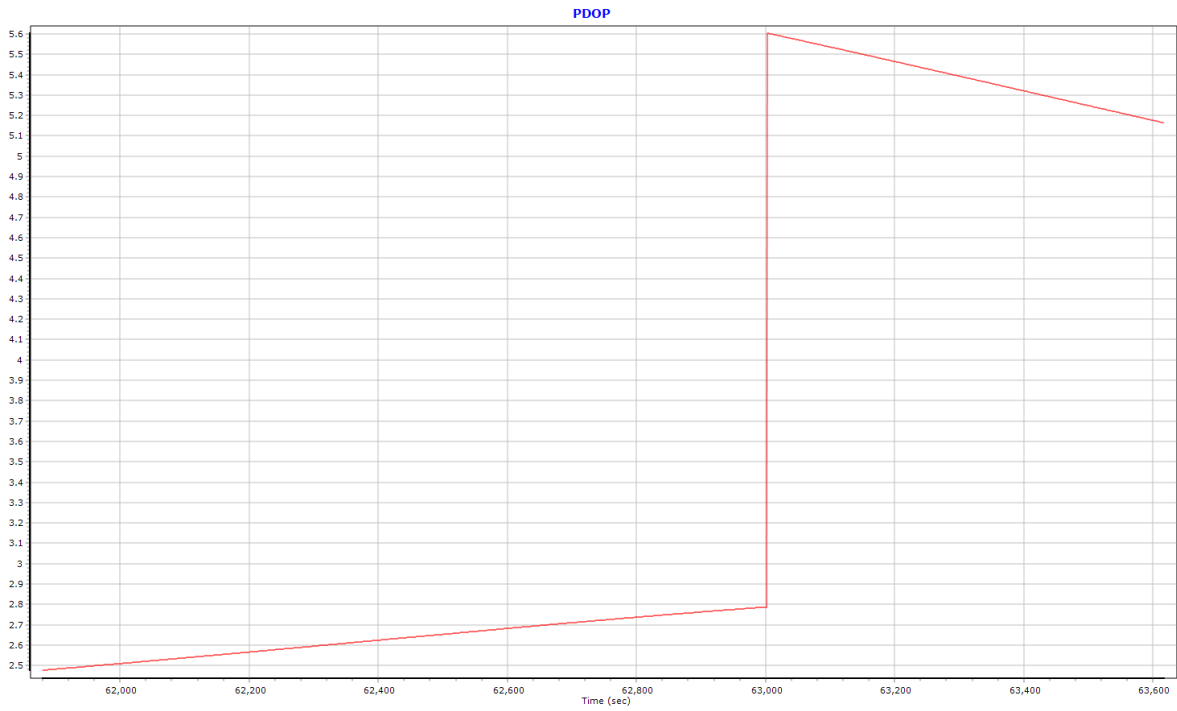




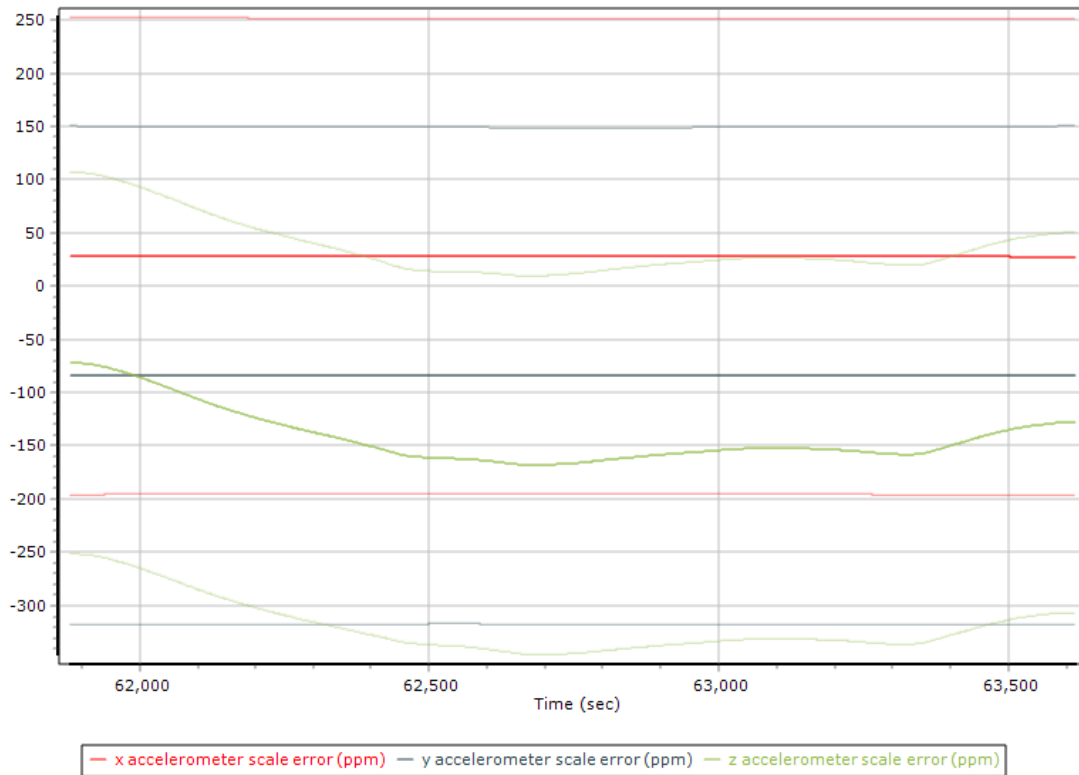
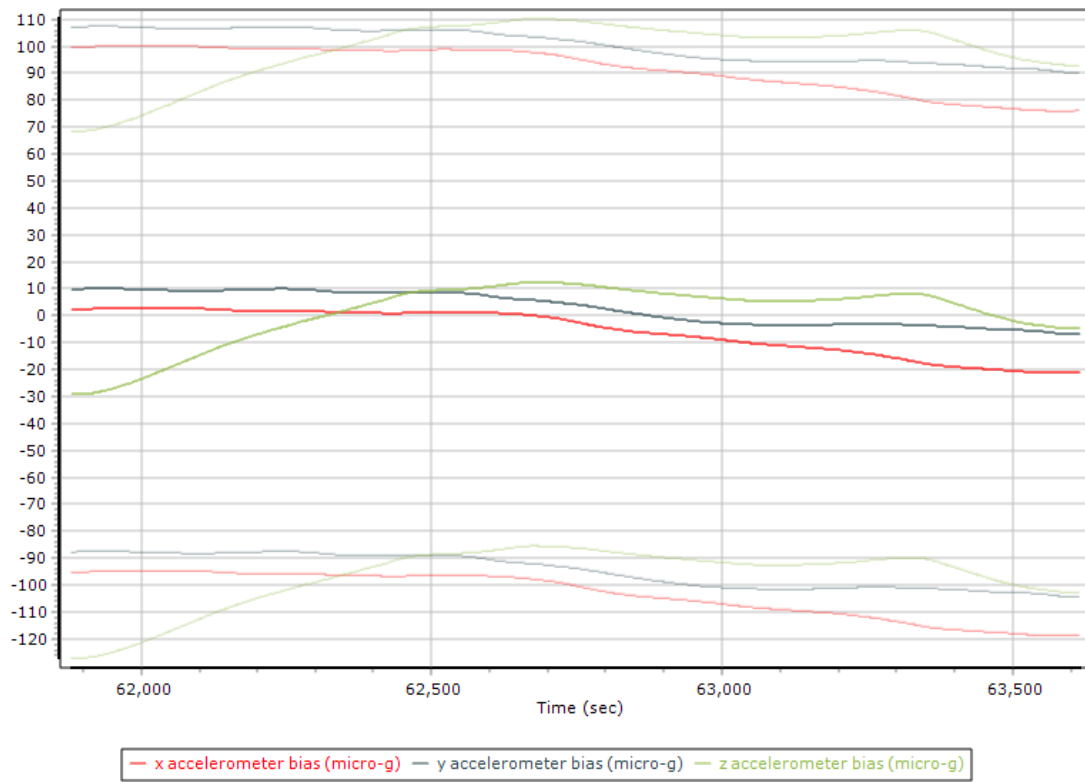


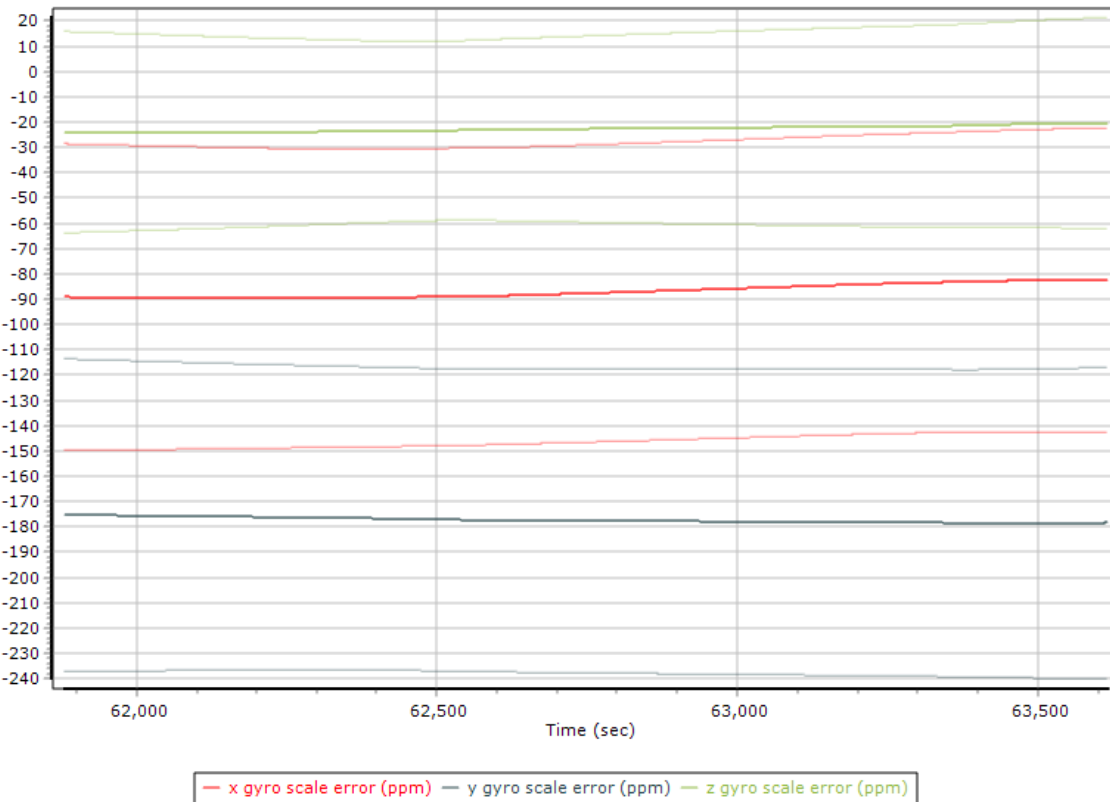
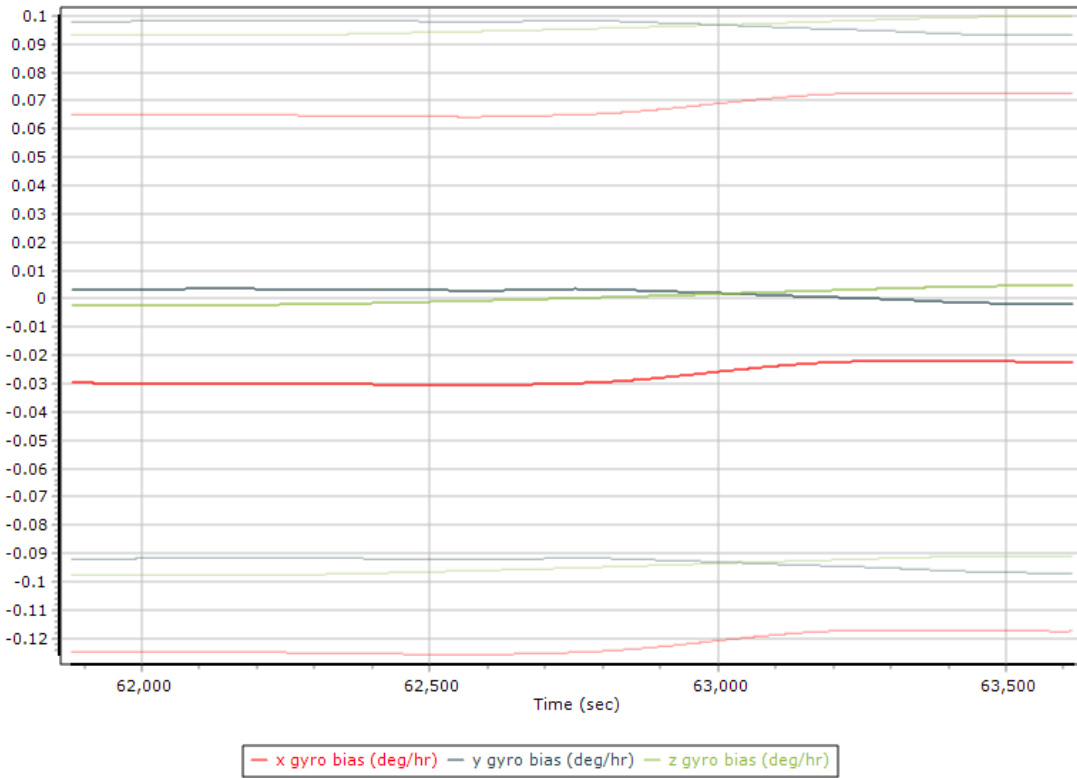




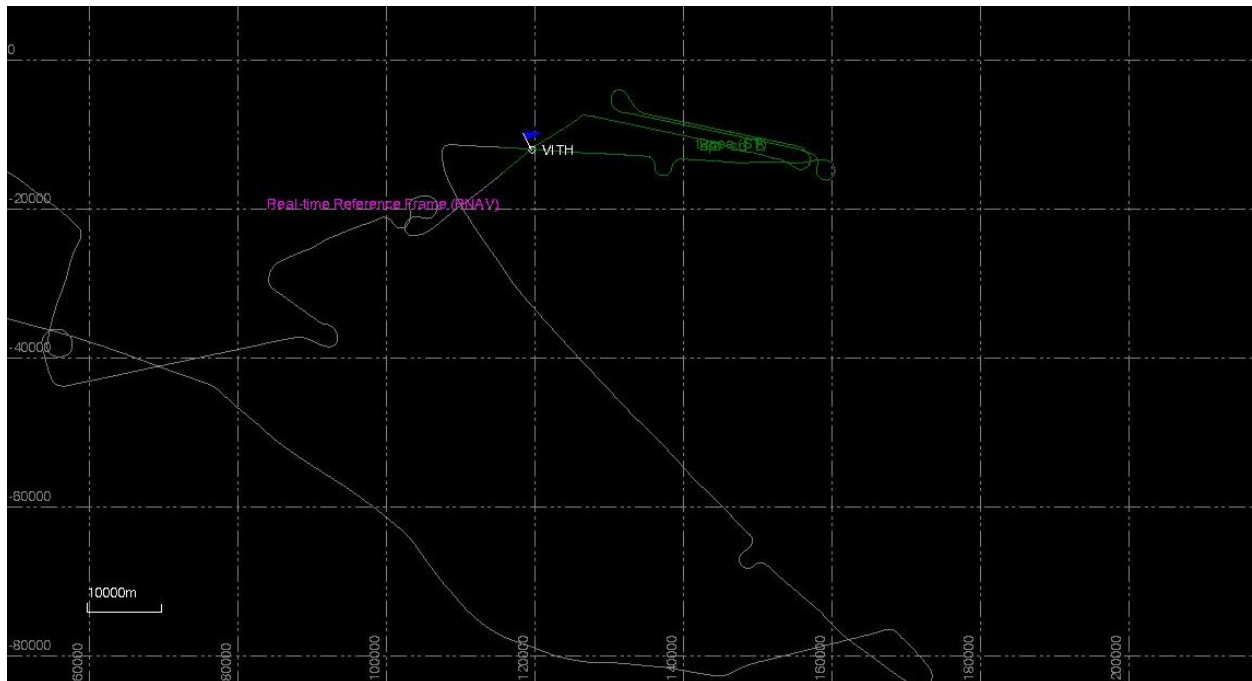


Sensor Errors





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Project Settings

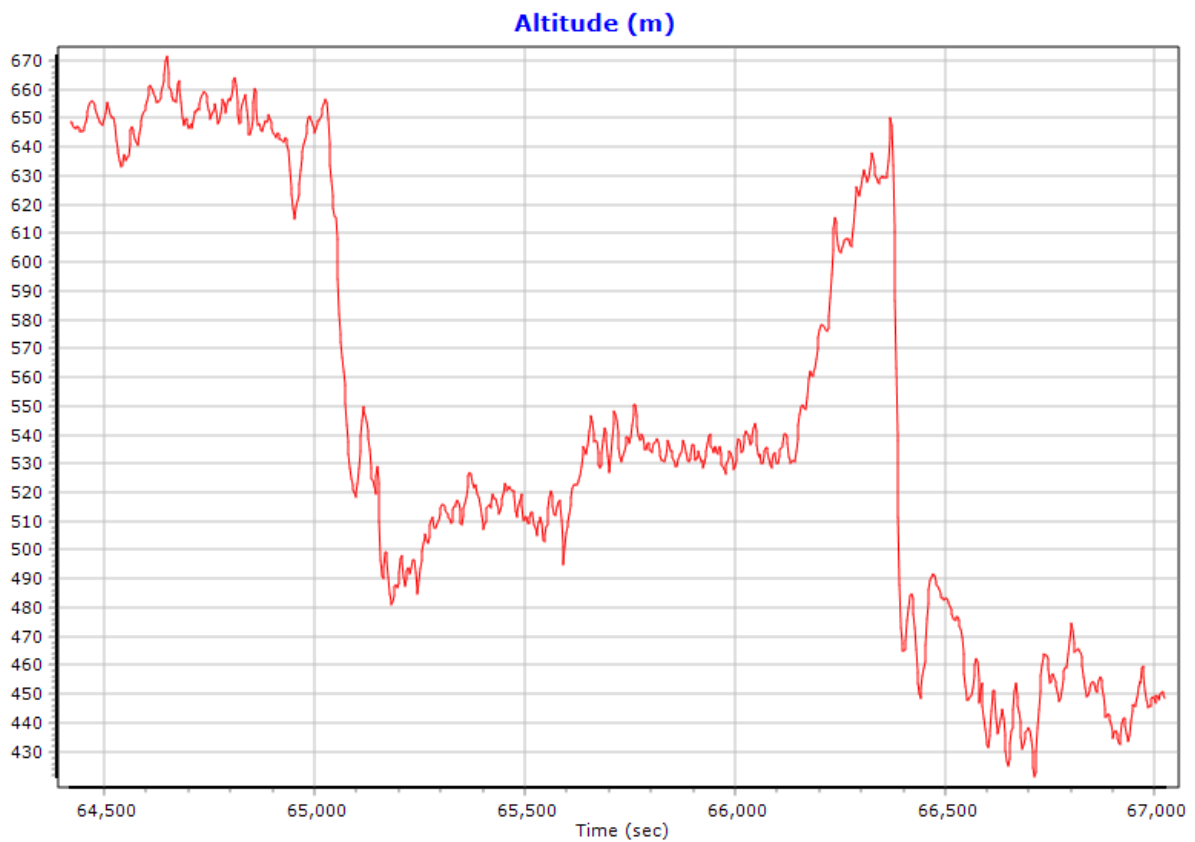
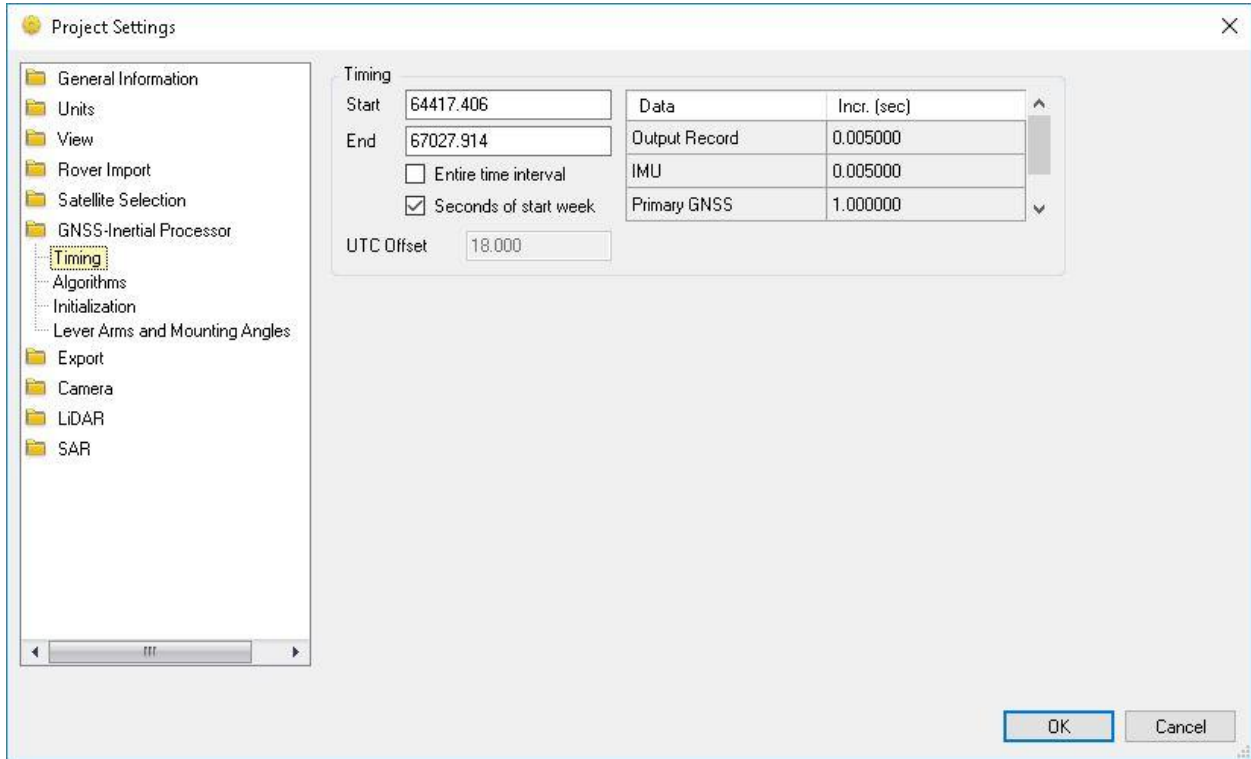
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LIDAR
- SAR

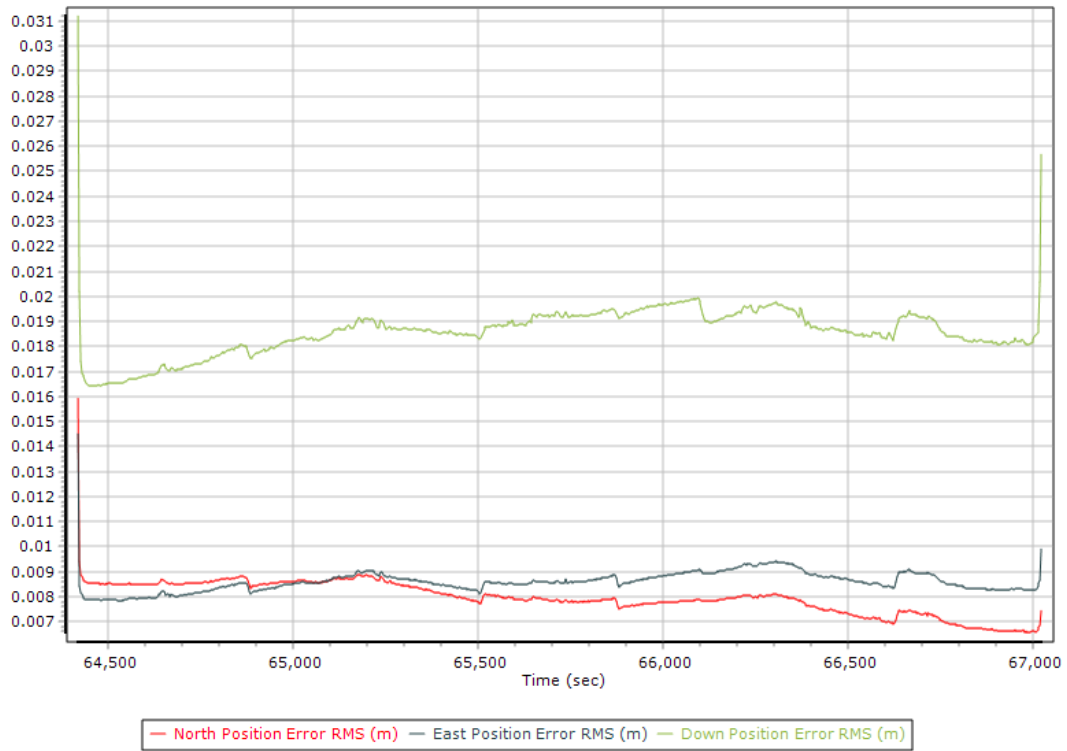
Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.049 m	0.003 m	-1.230 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

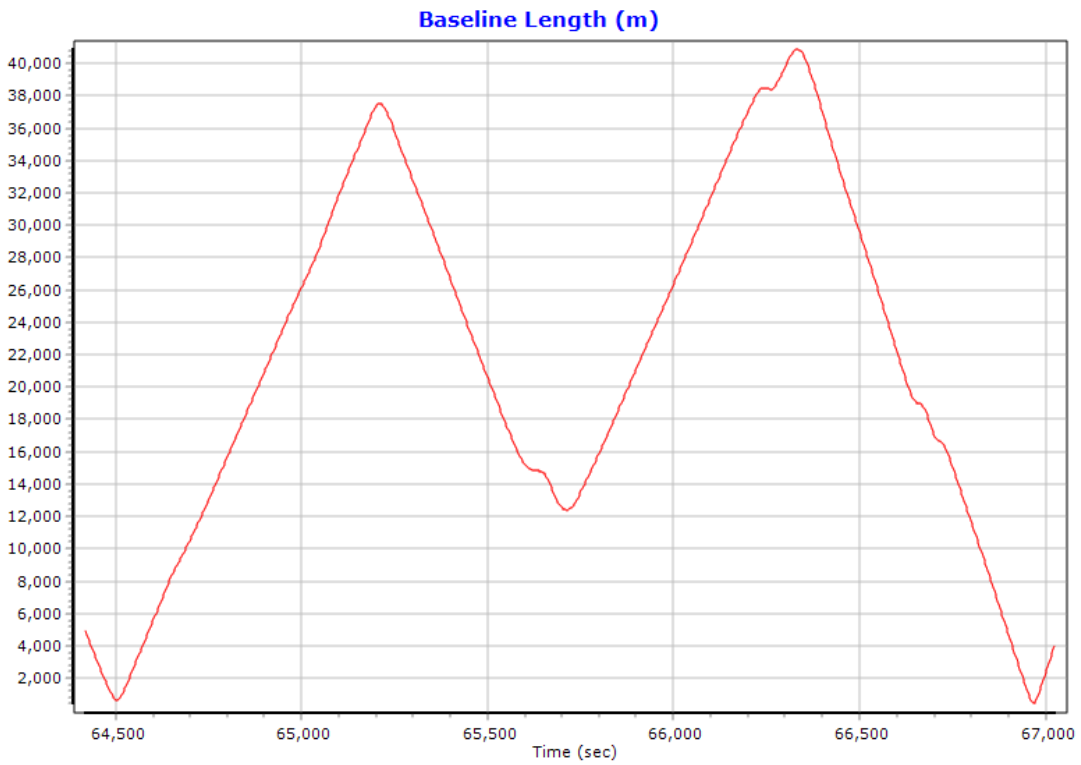
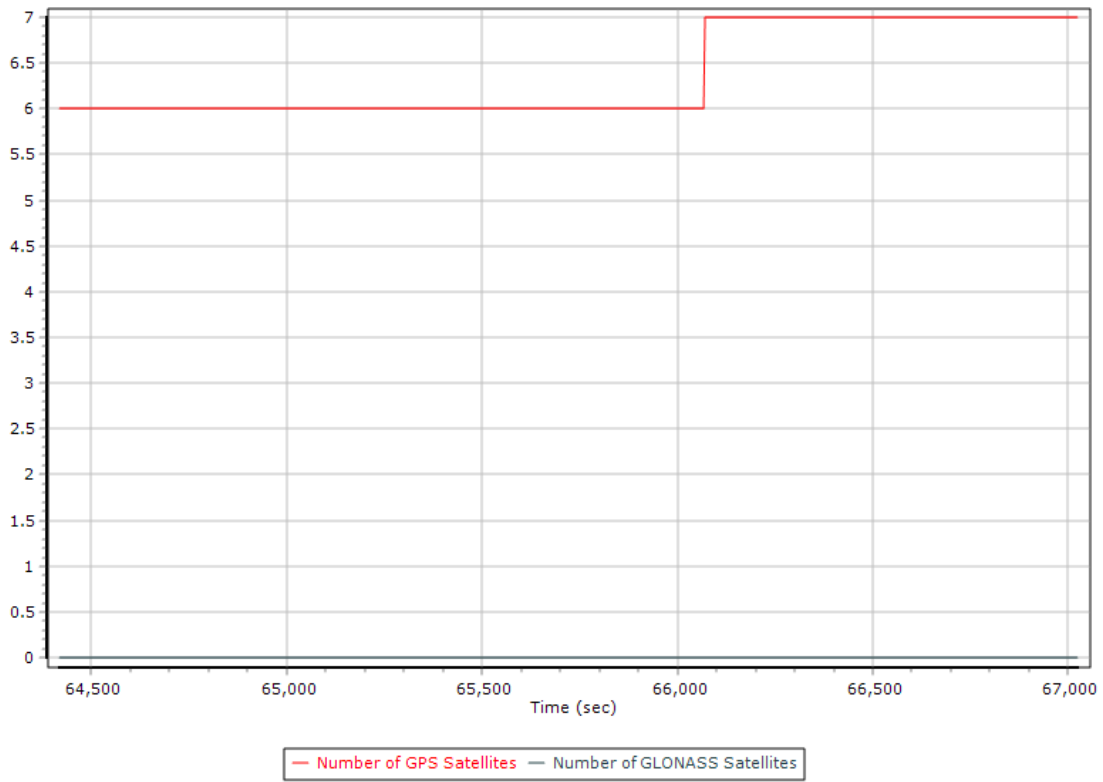
Standard Deviation: <3cm 10cm 50cm 1m 10m

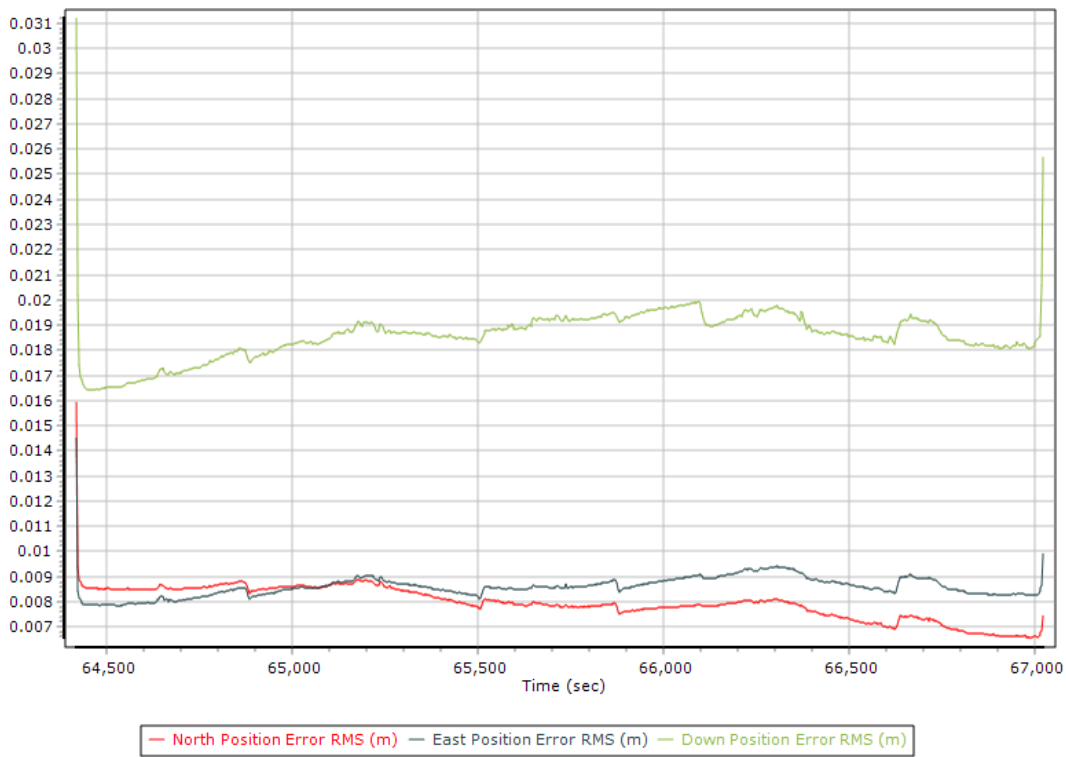
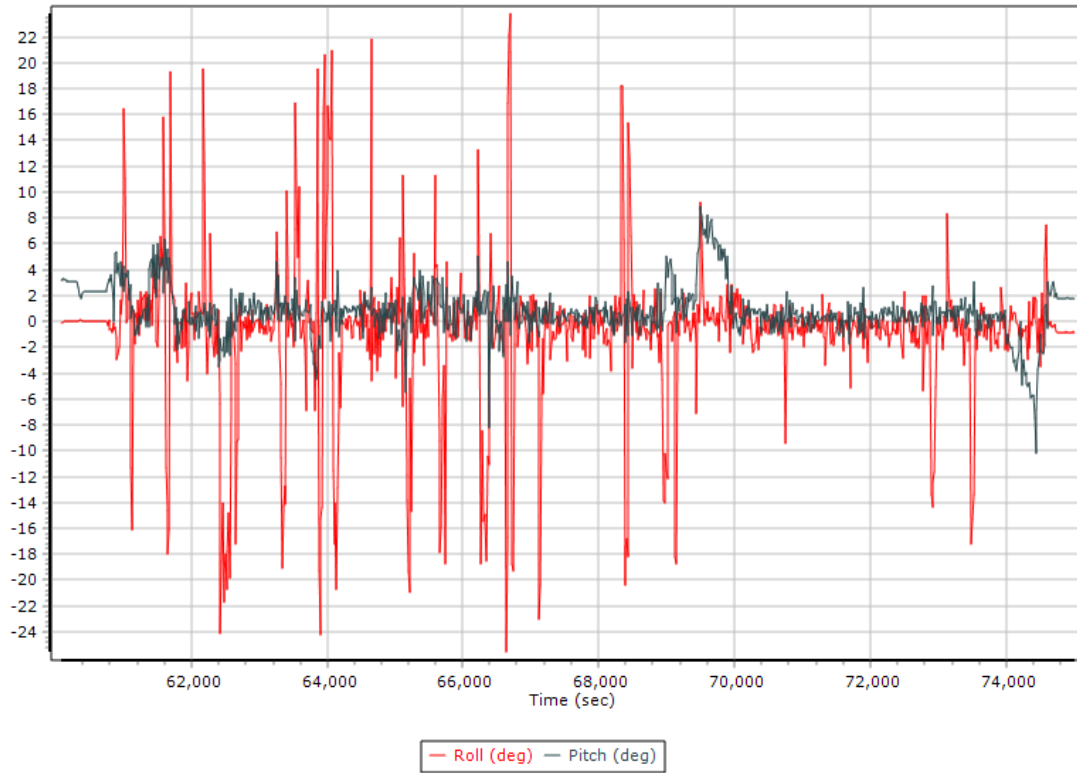
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

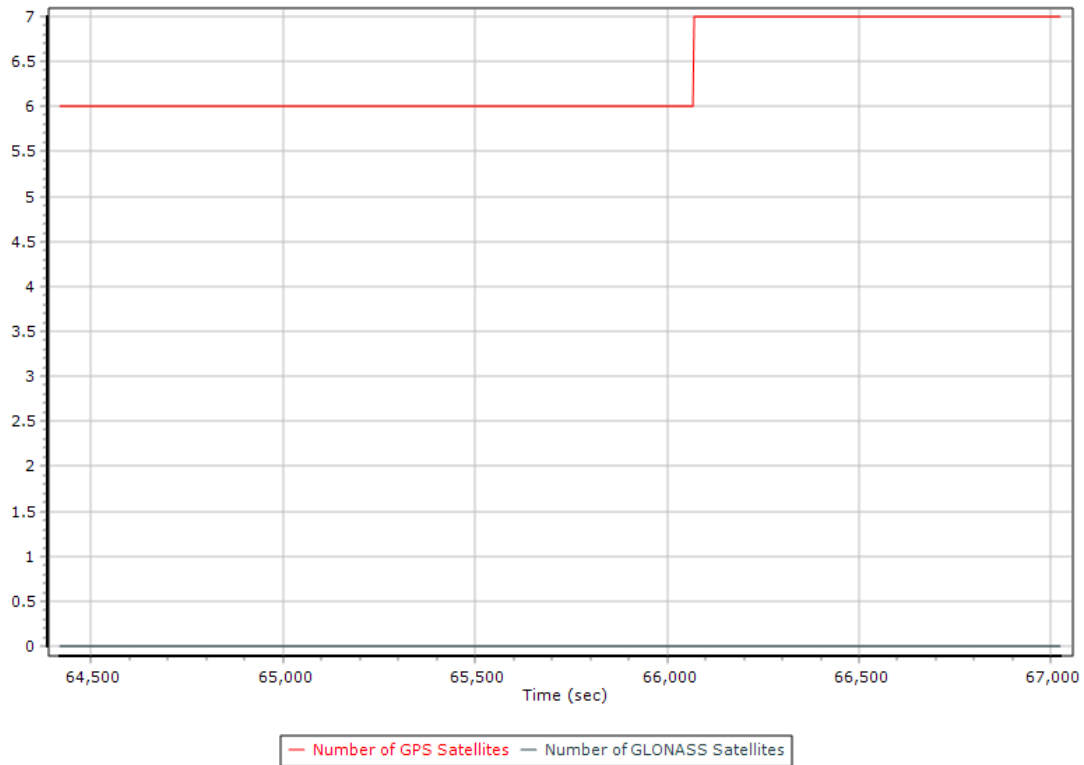
OK Cancel

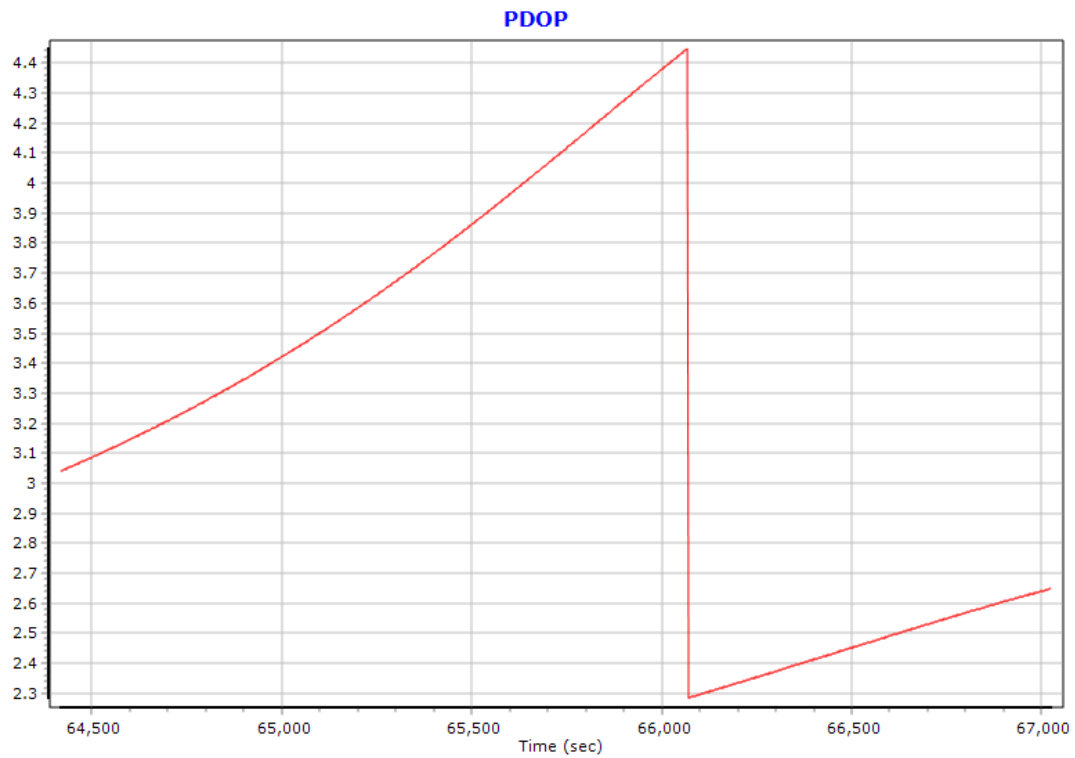
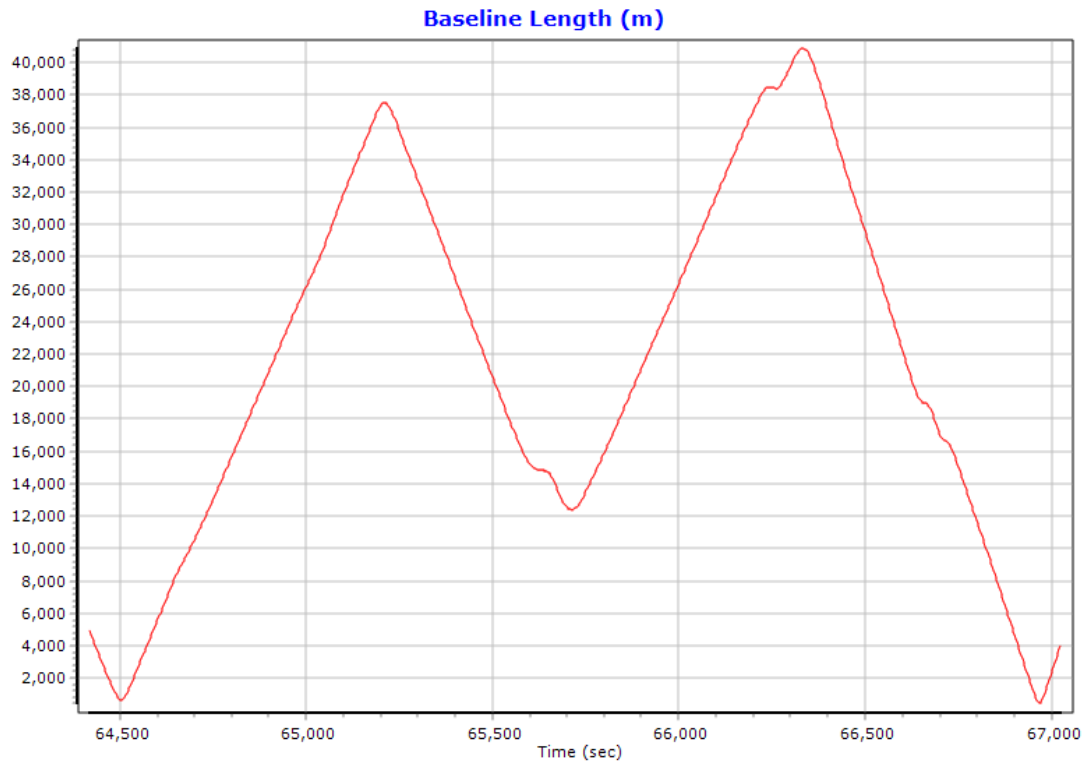


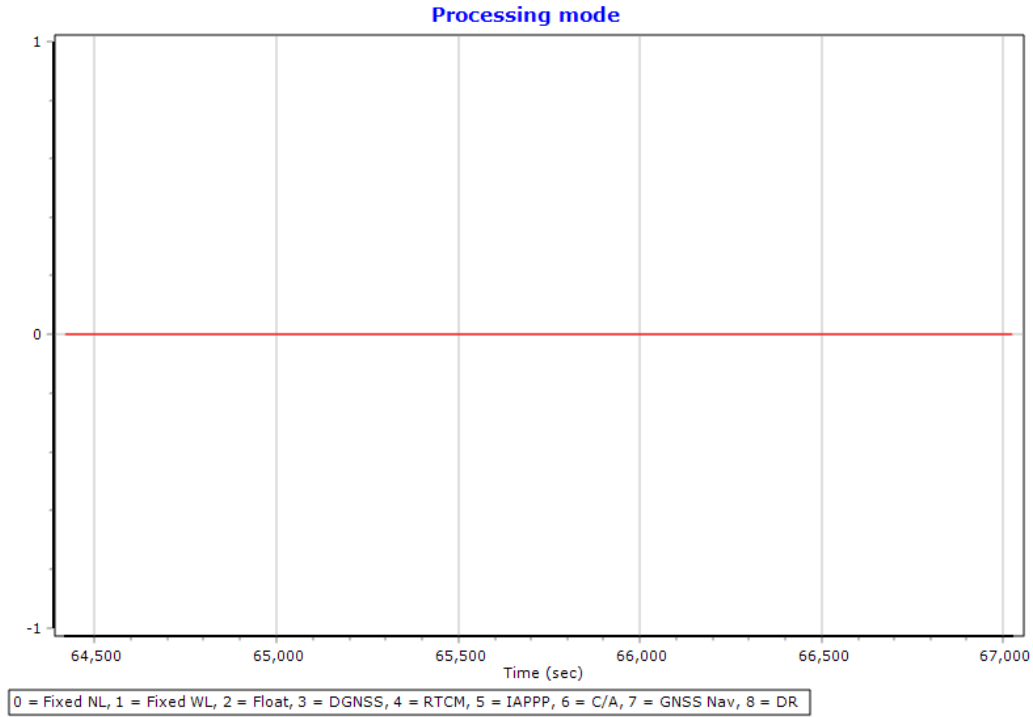


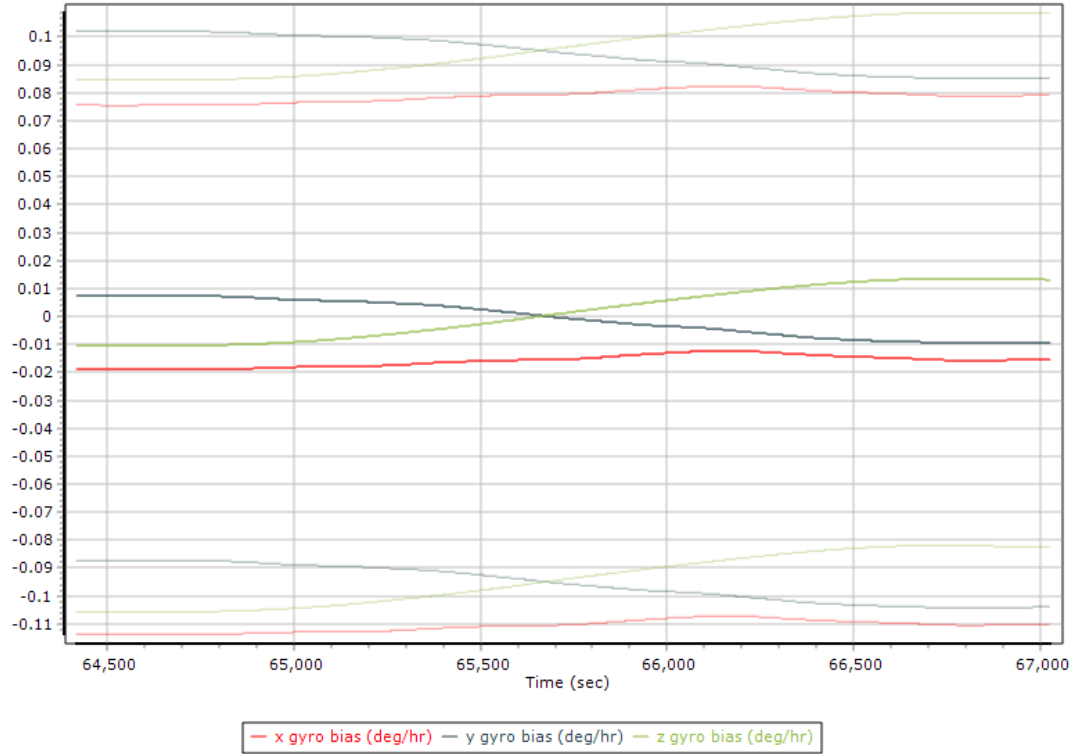
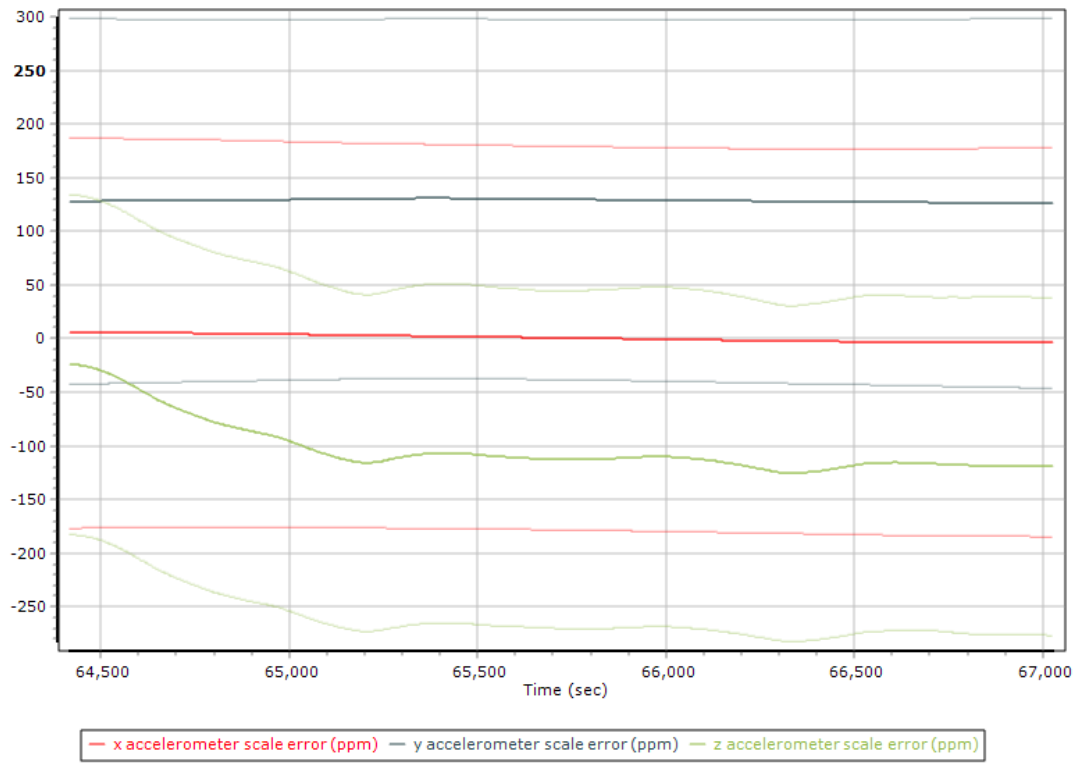


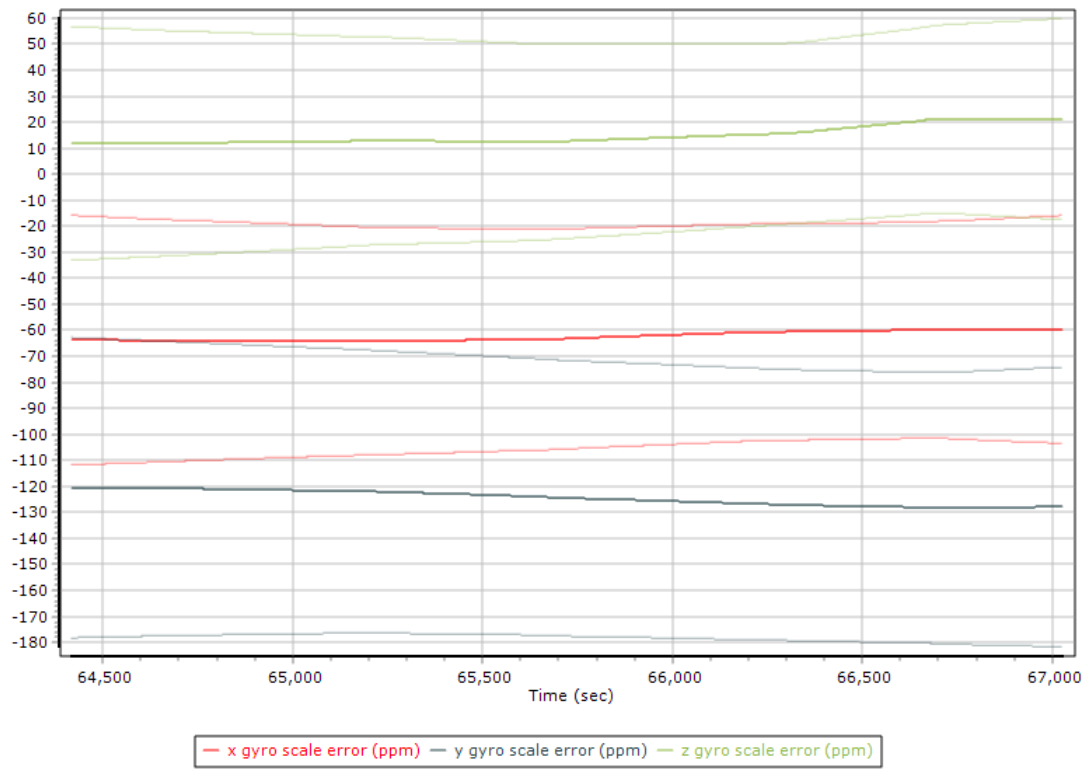




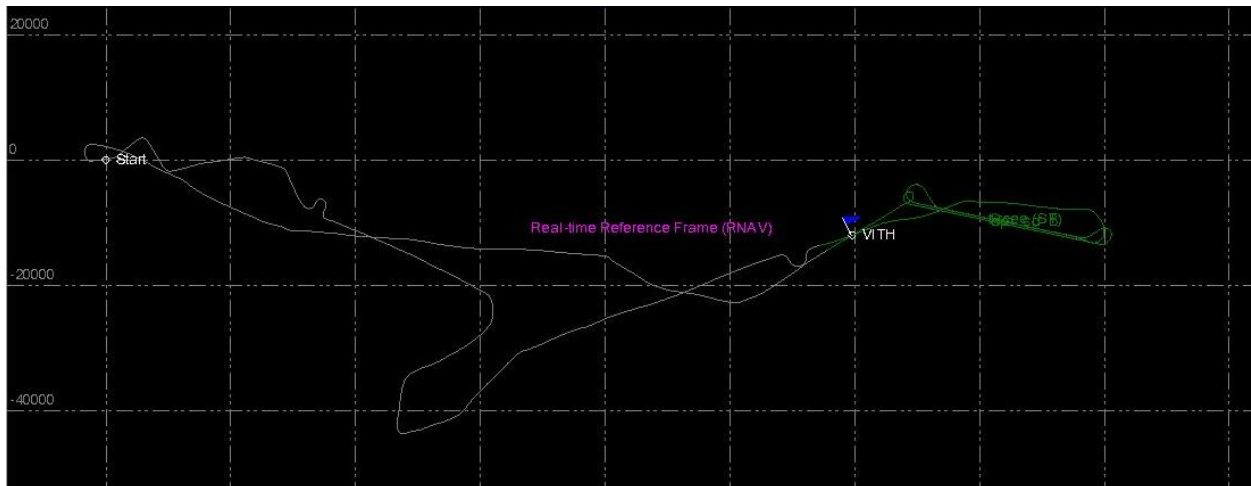


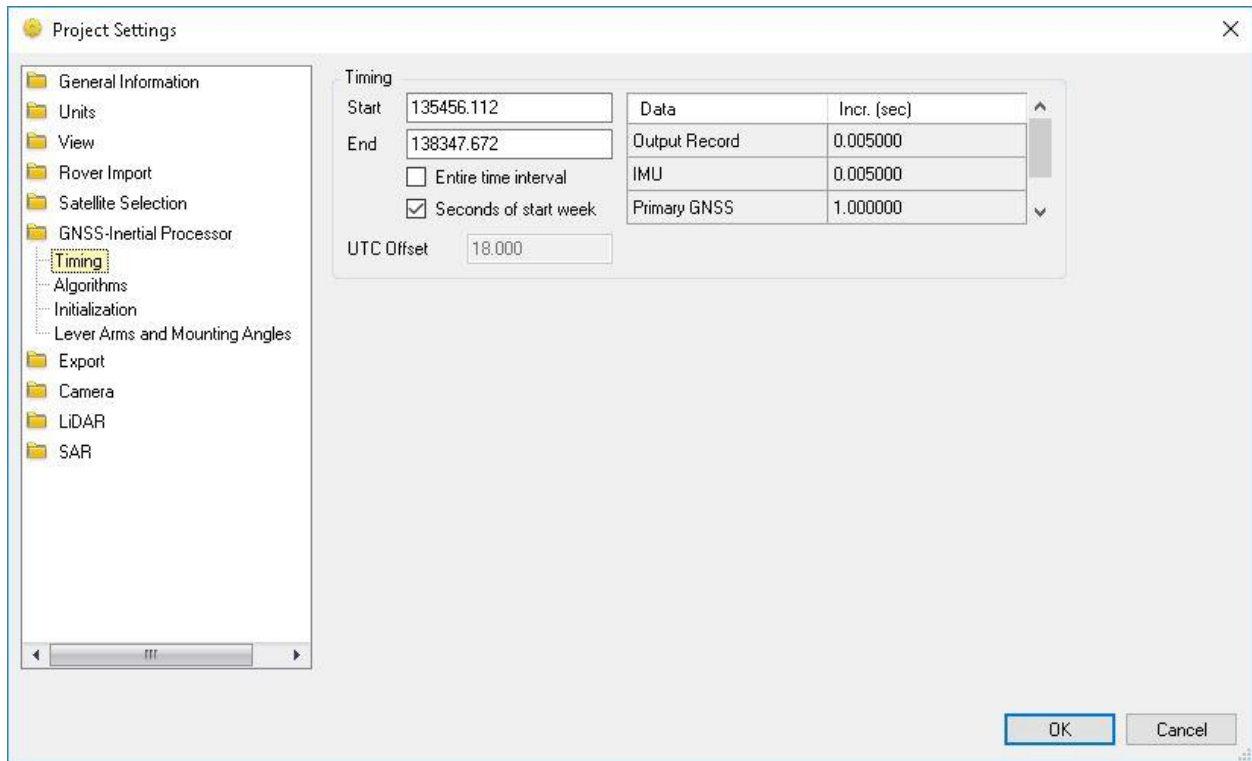
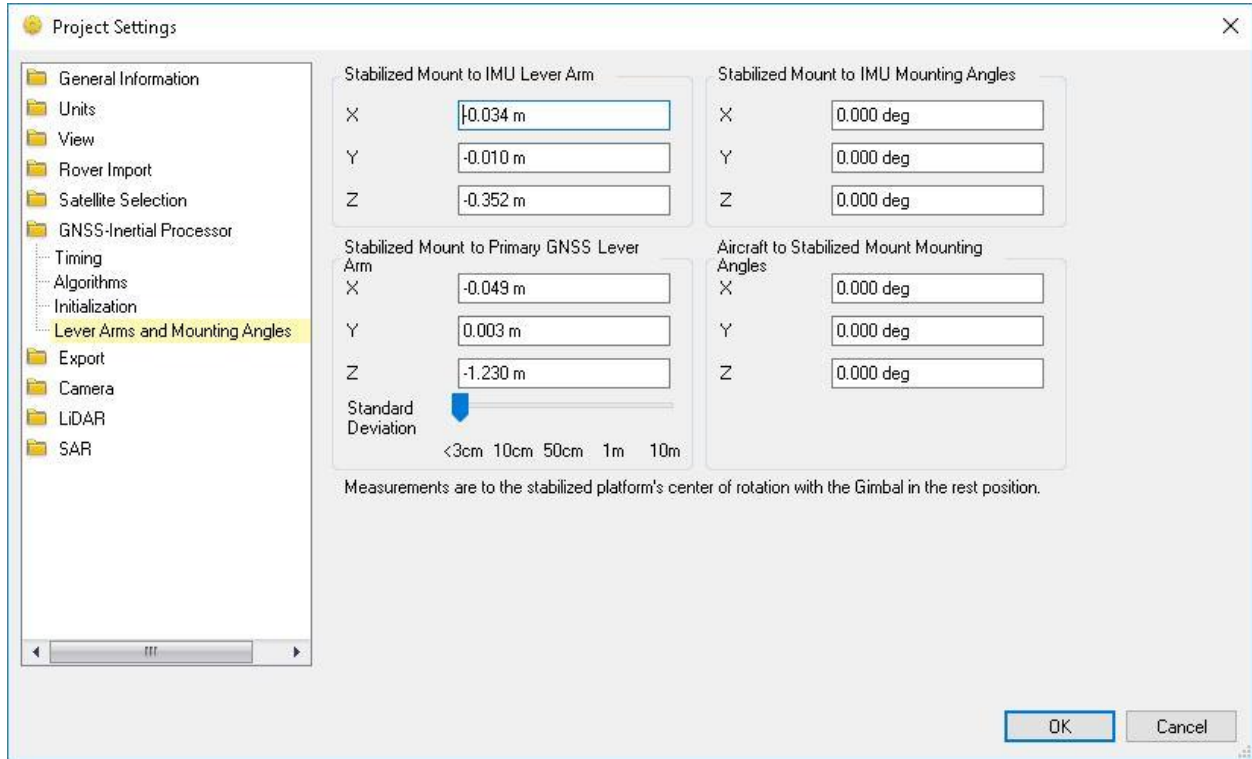


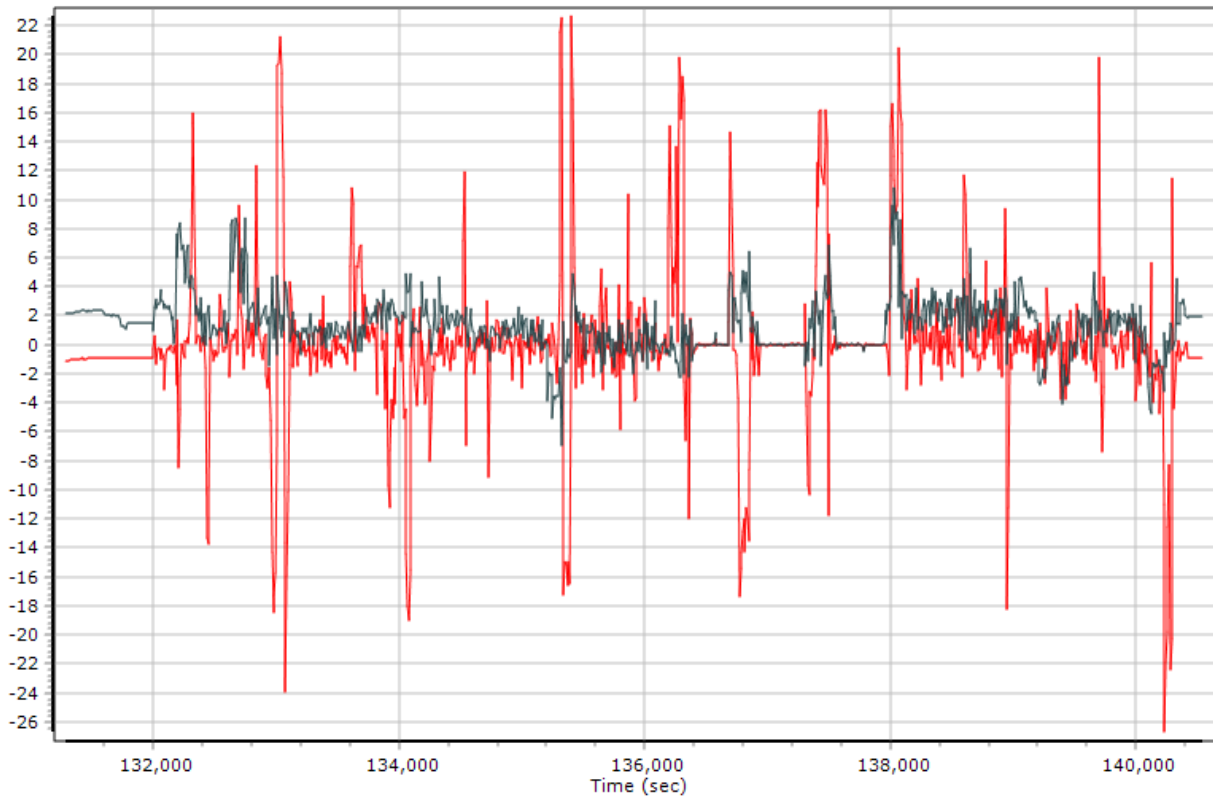
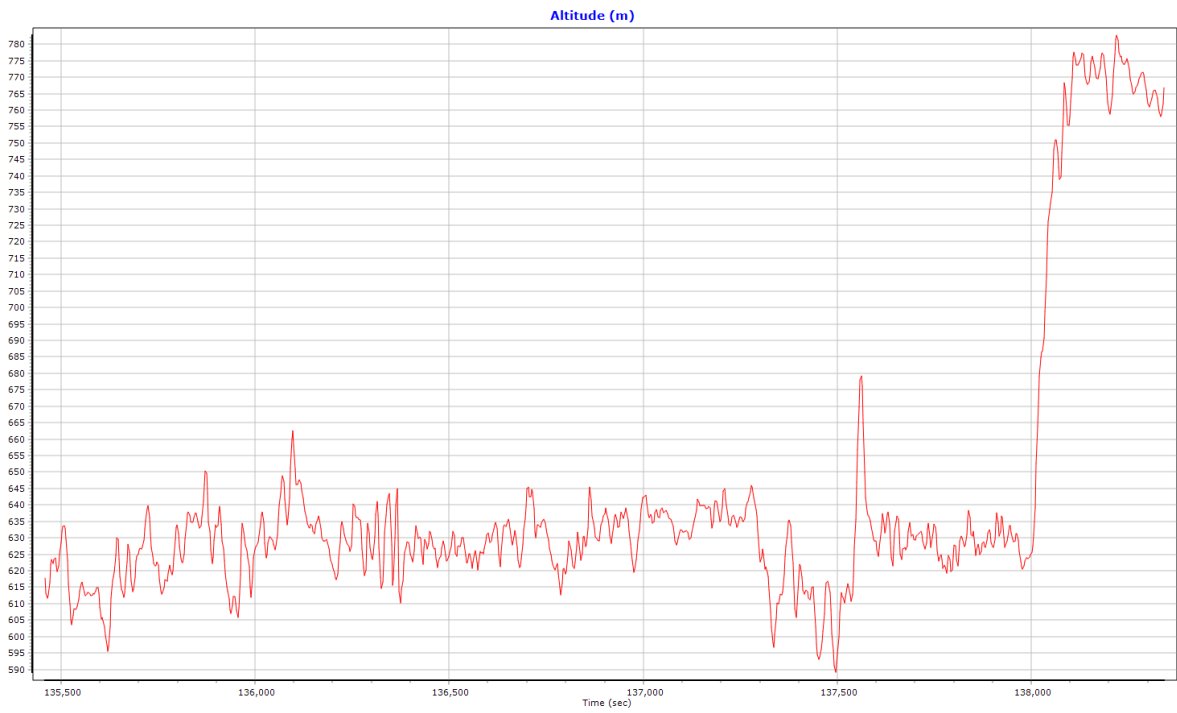




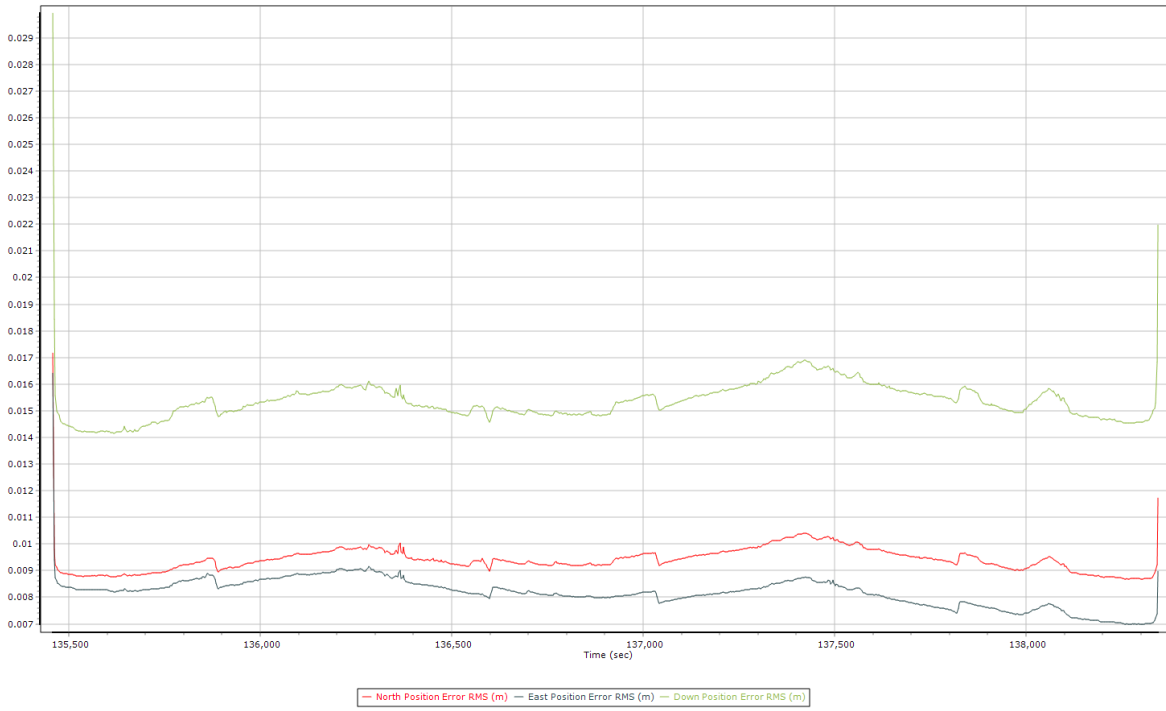
45A18288A

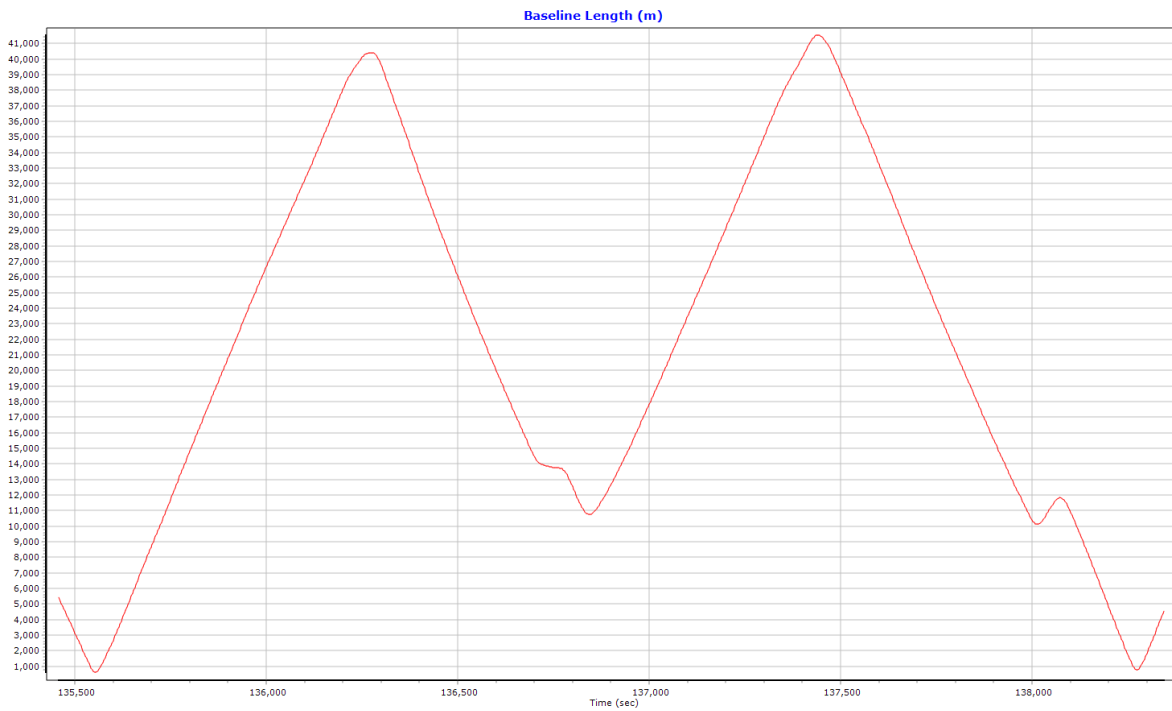
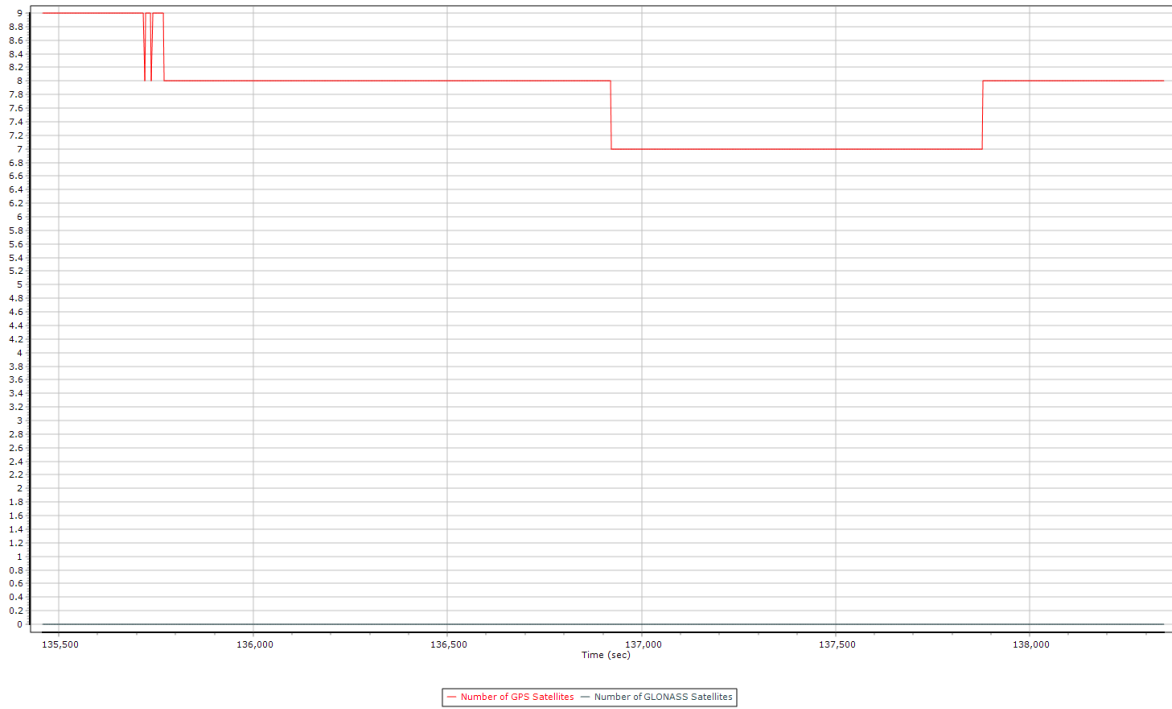


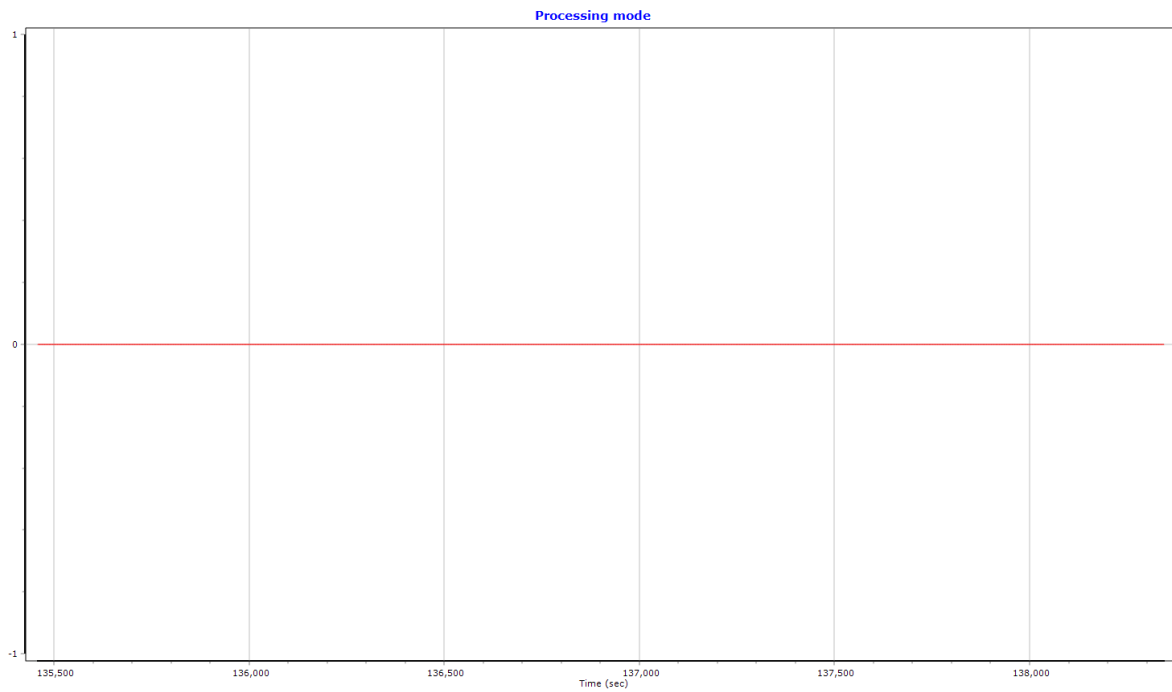
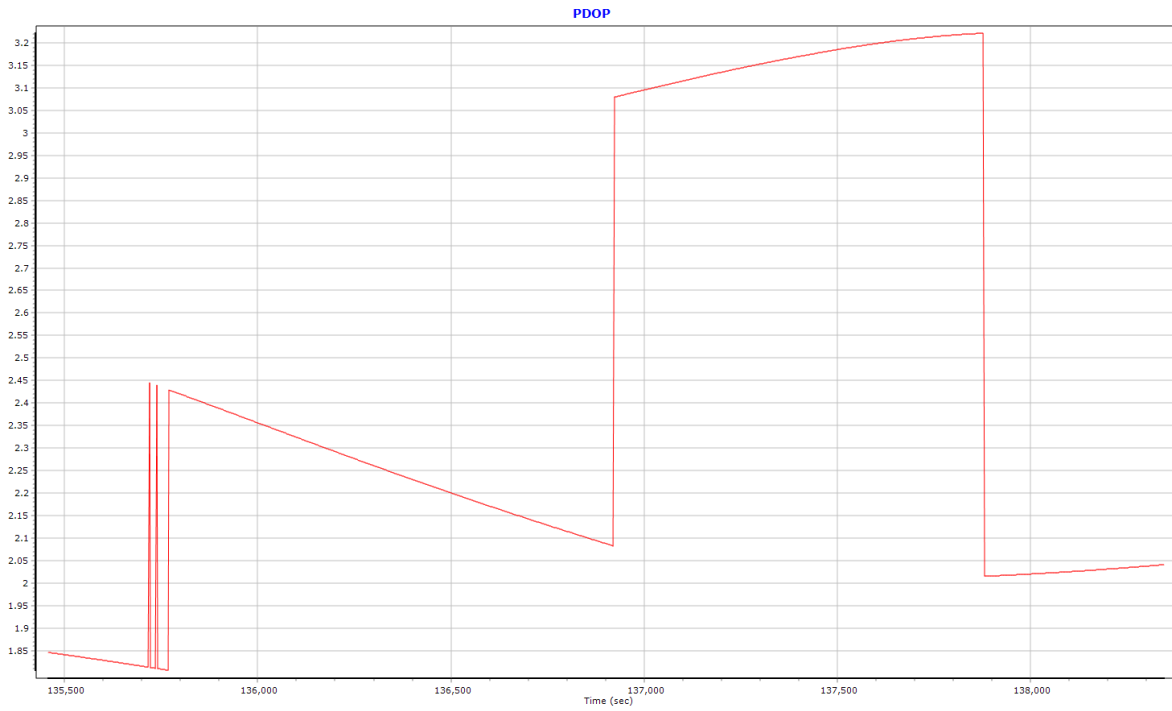




— Roll (deg) — Pitch (deg)

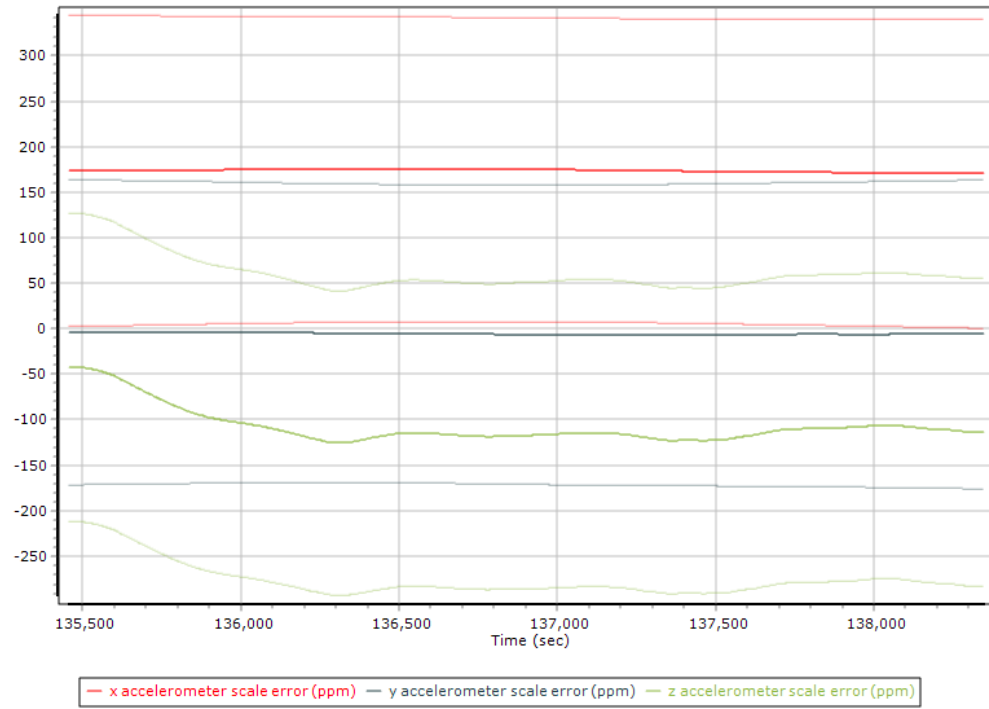
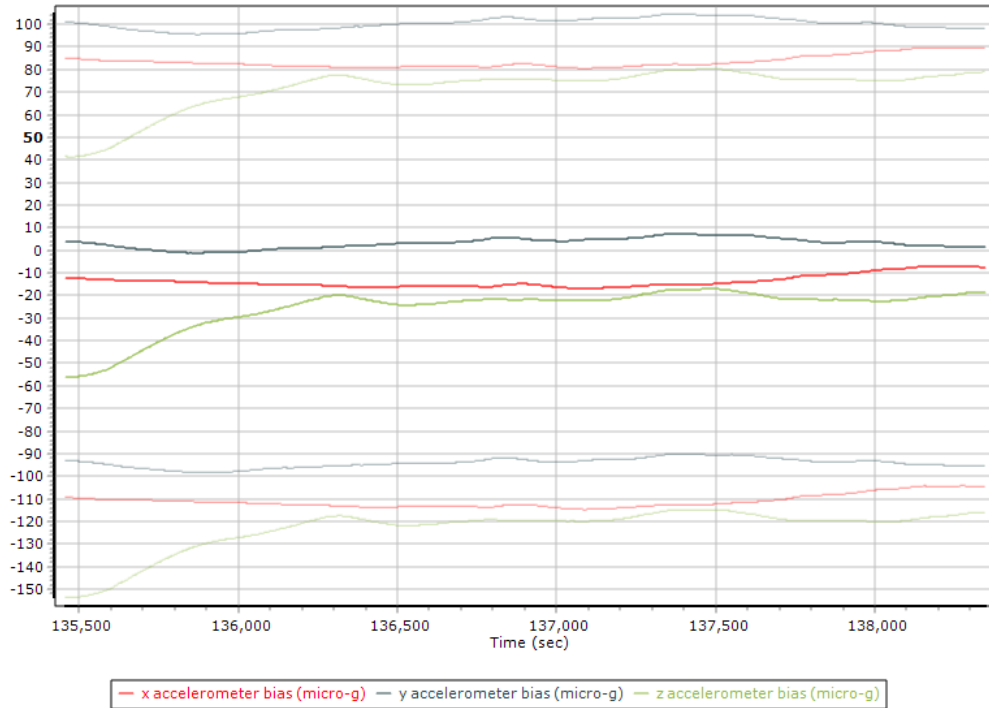


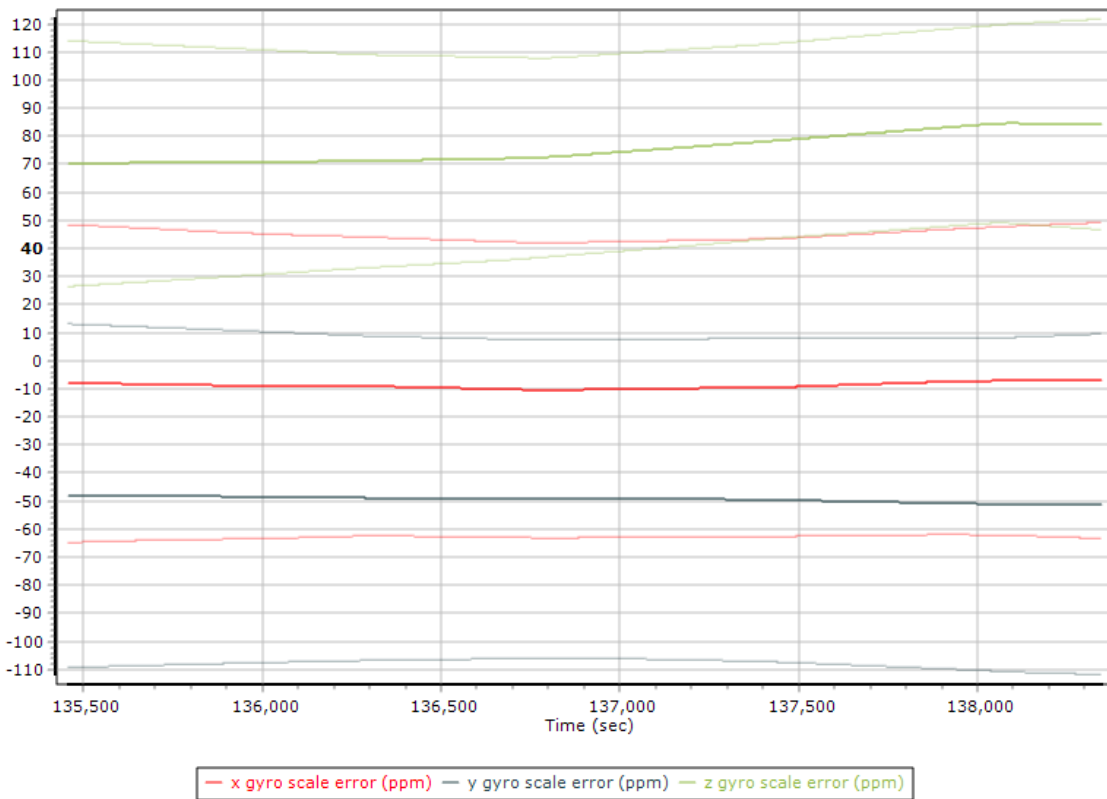
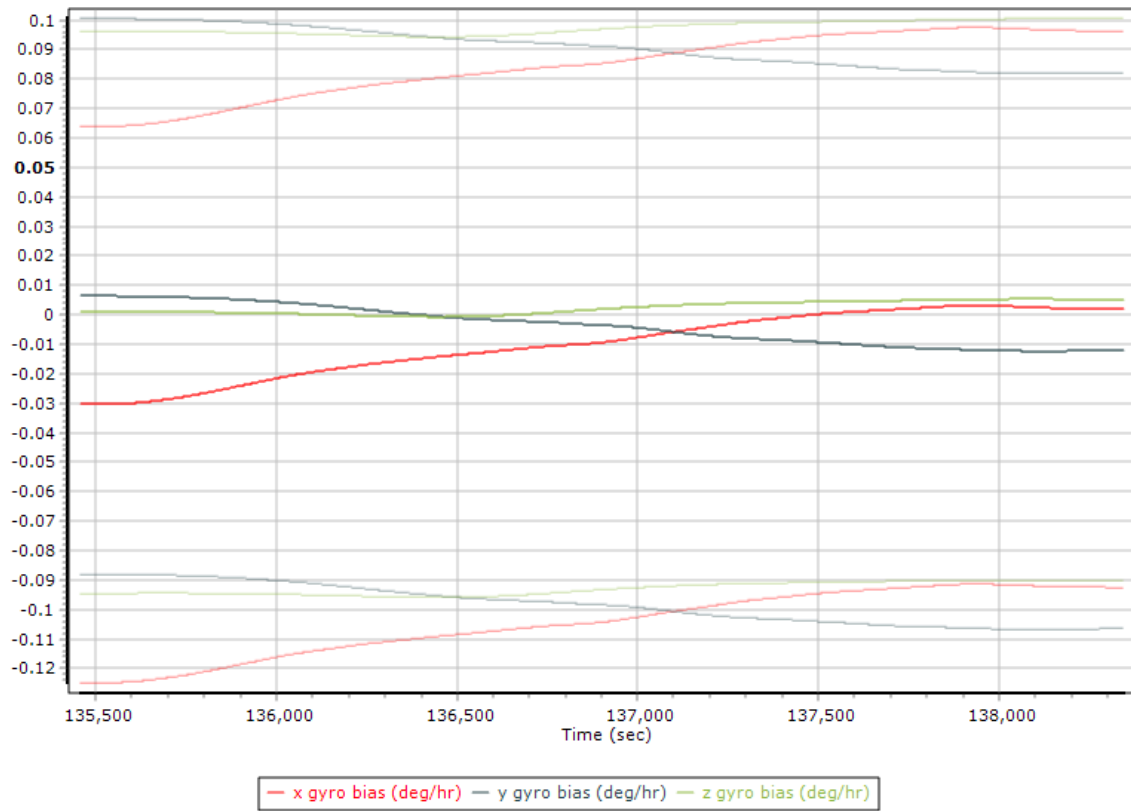




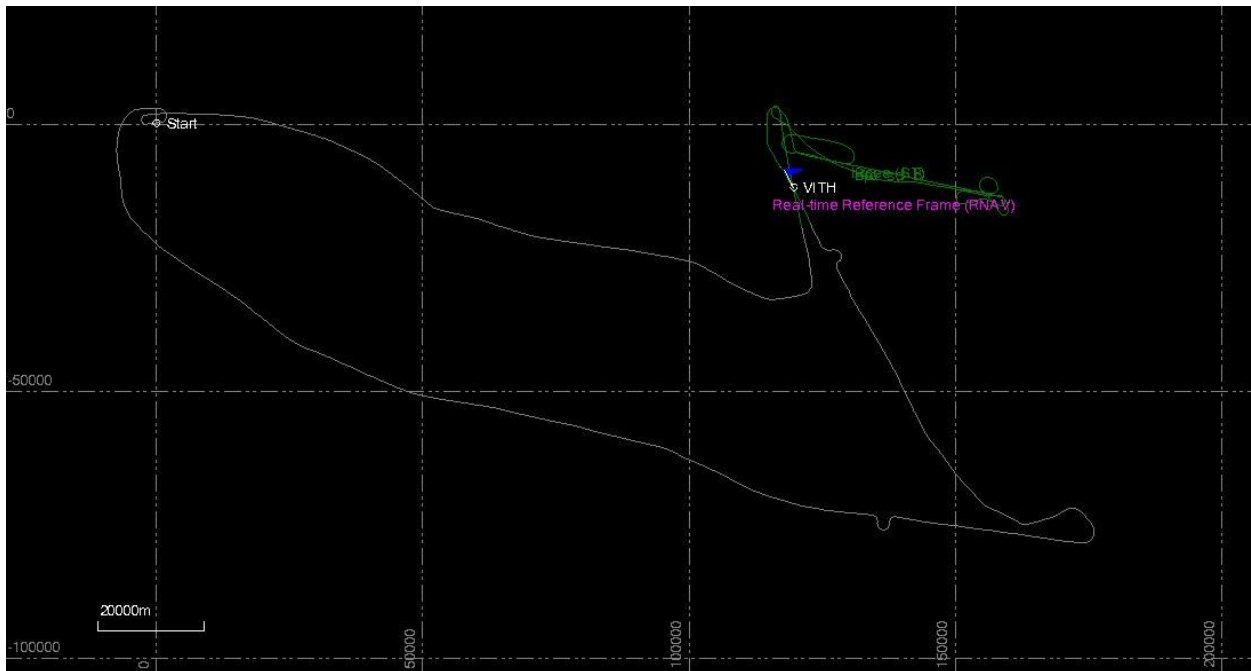
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





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Project Settings

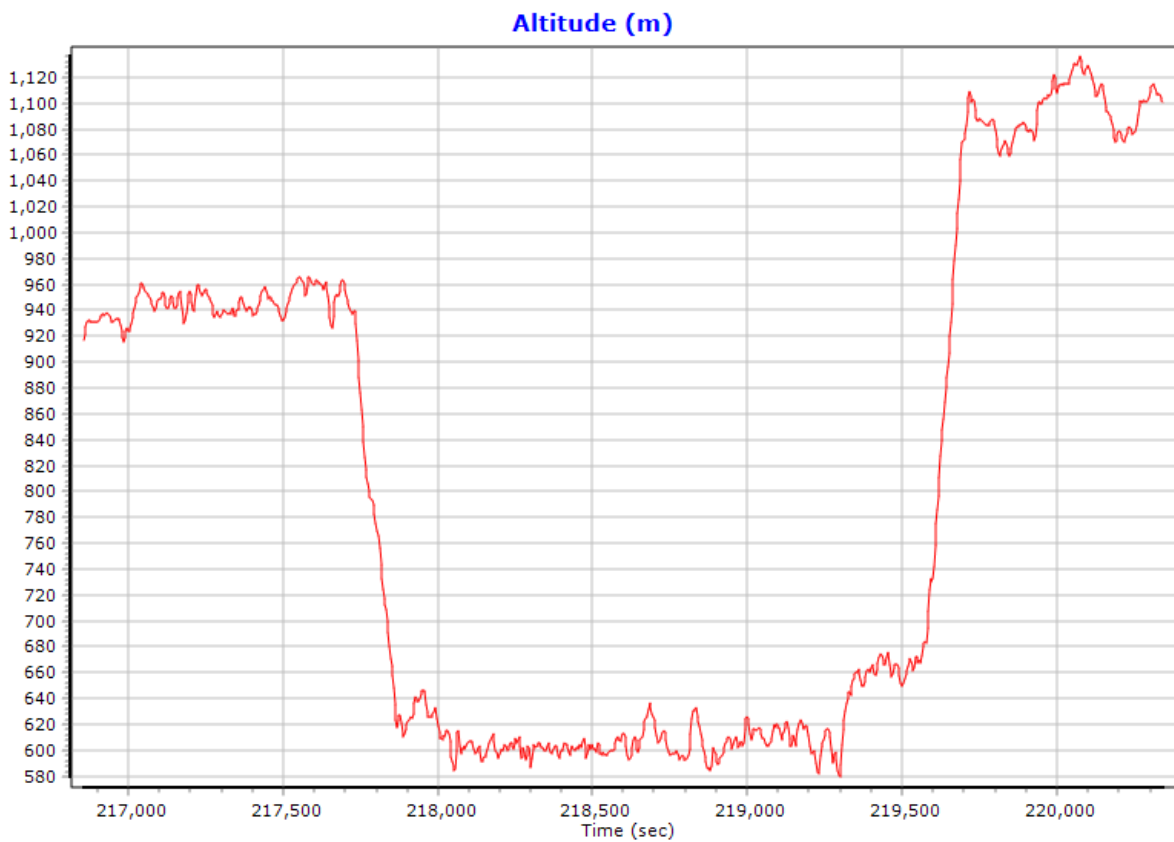
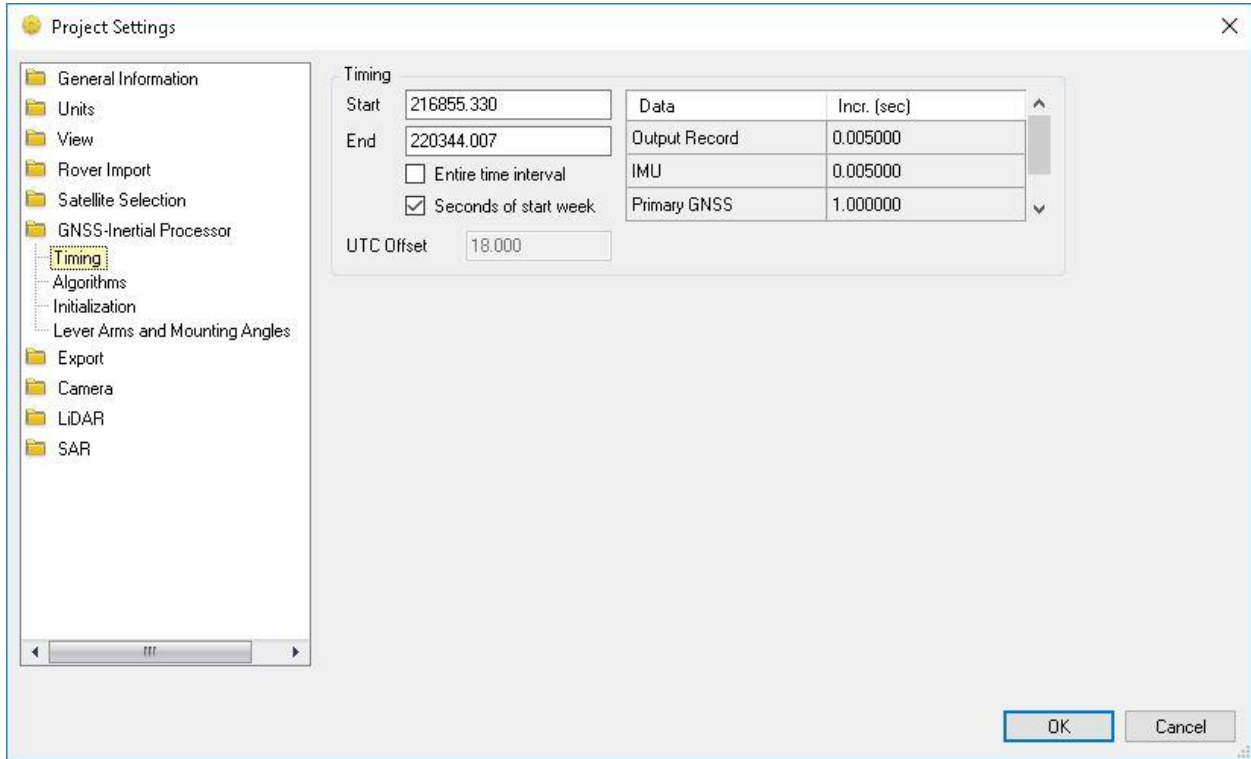
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LIDAR
- SAR

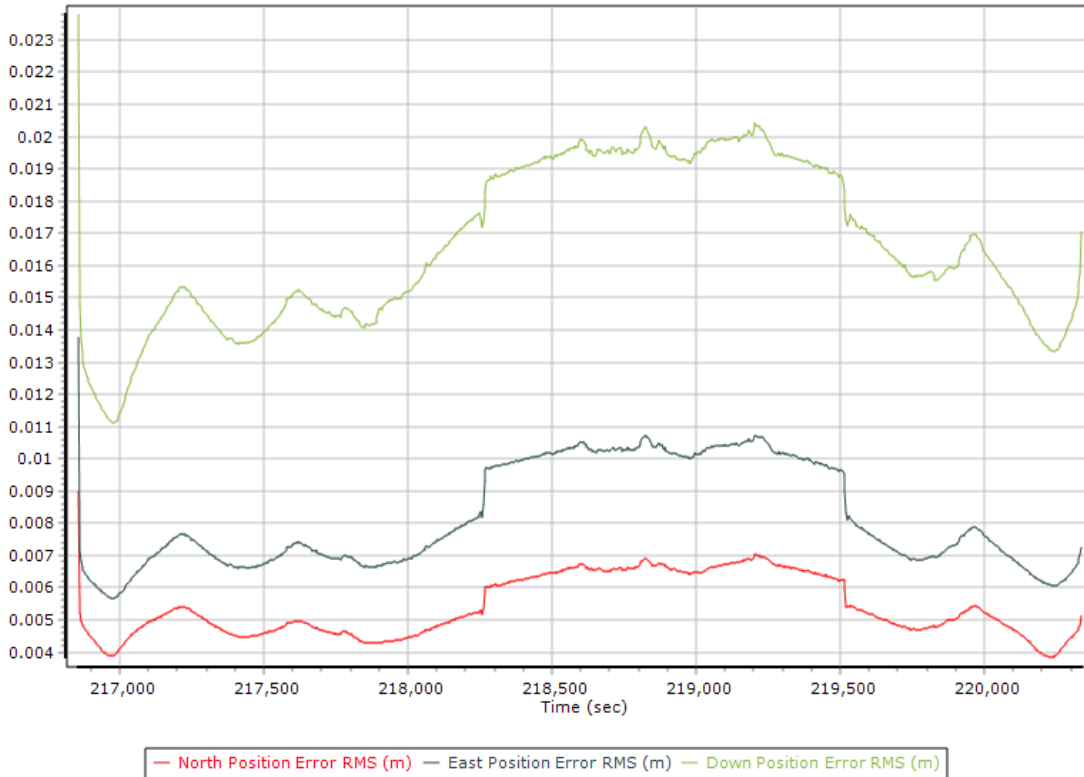
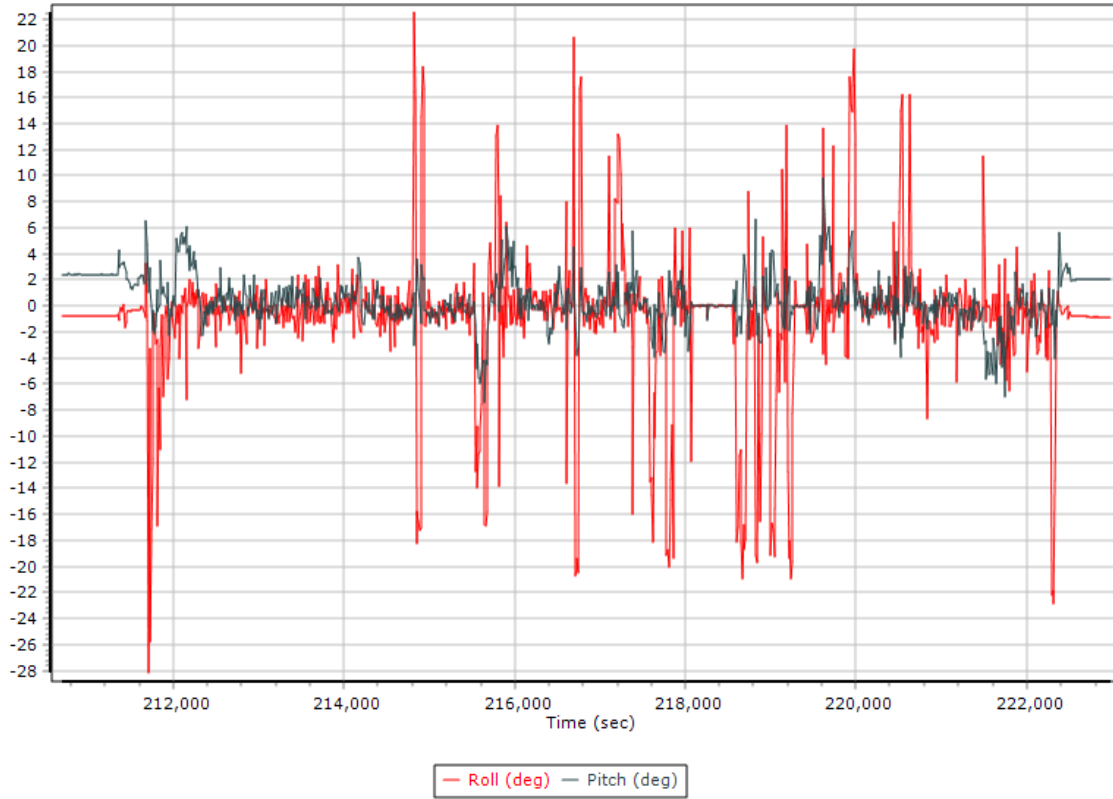
Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.049 m	0.003 m	-1.230 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

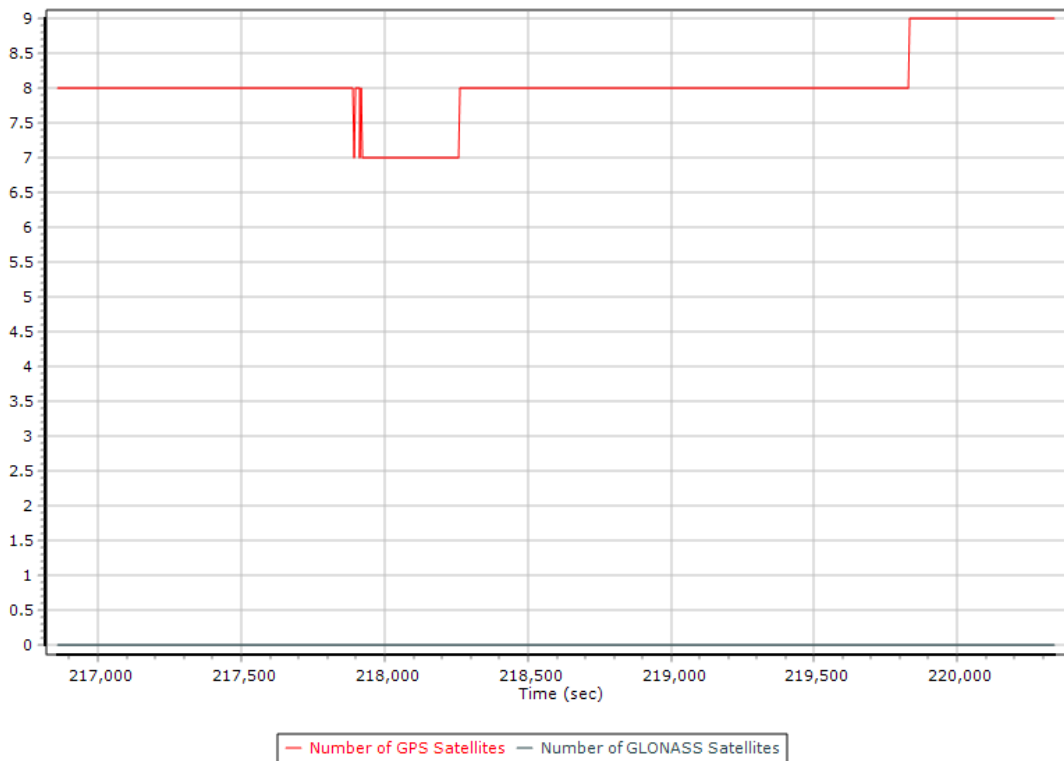
Standard Deviation: <3cm 10cm 50cm 1m 10m

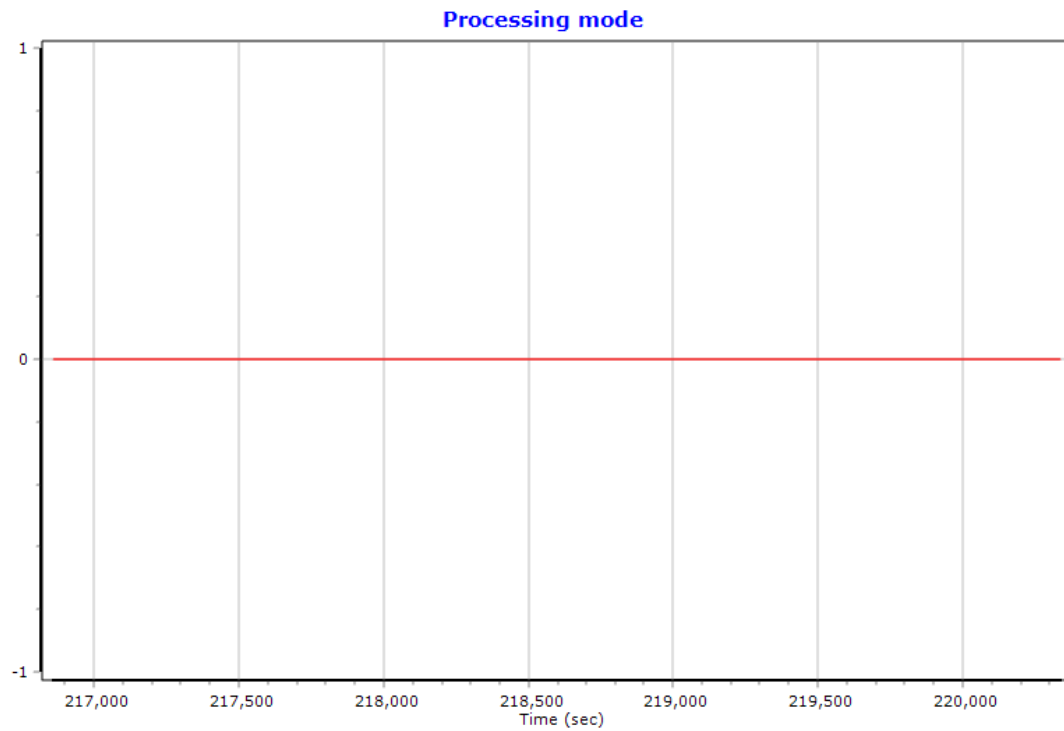
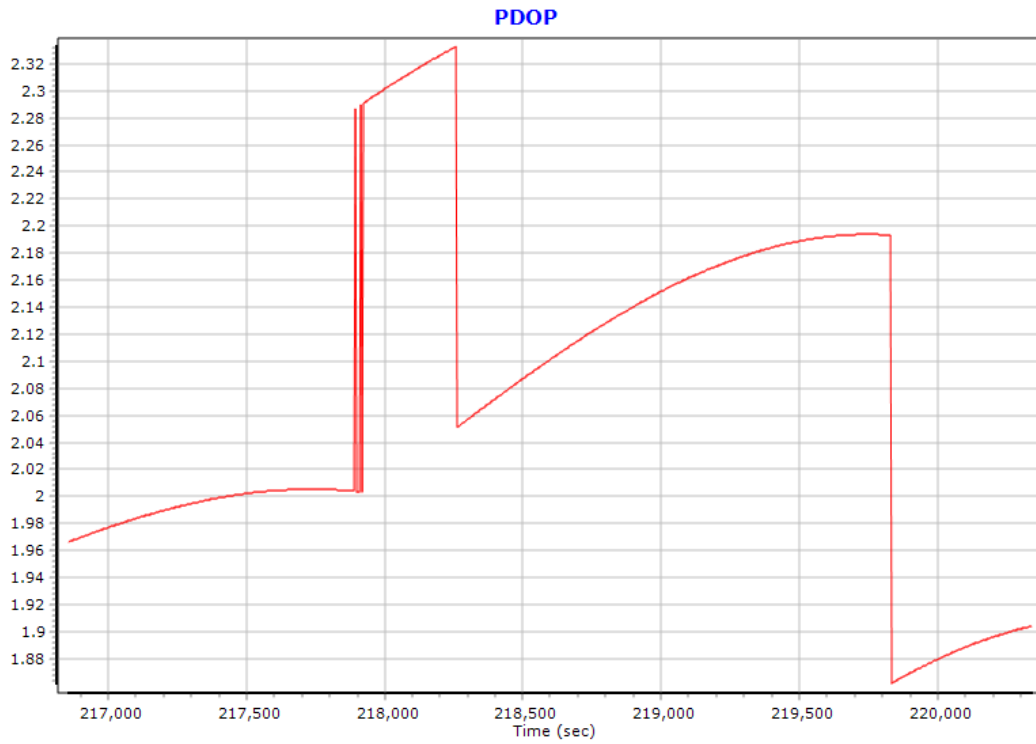
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

OK Cancel



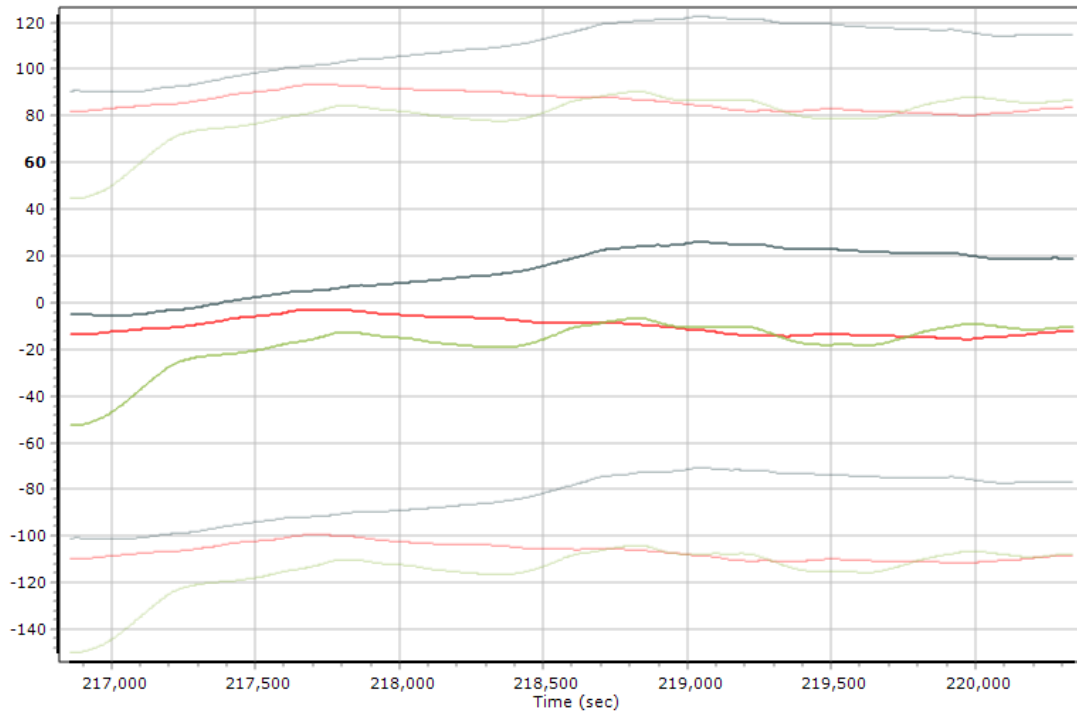




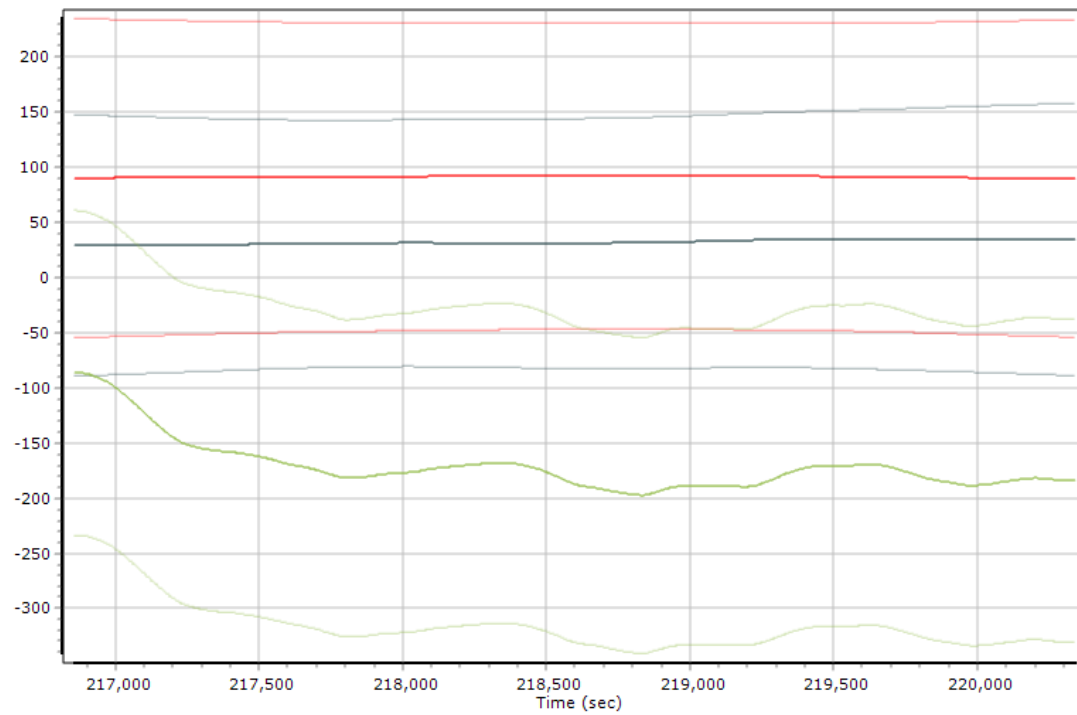


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

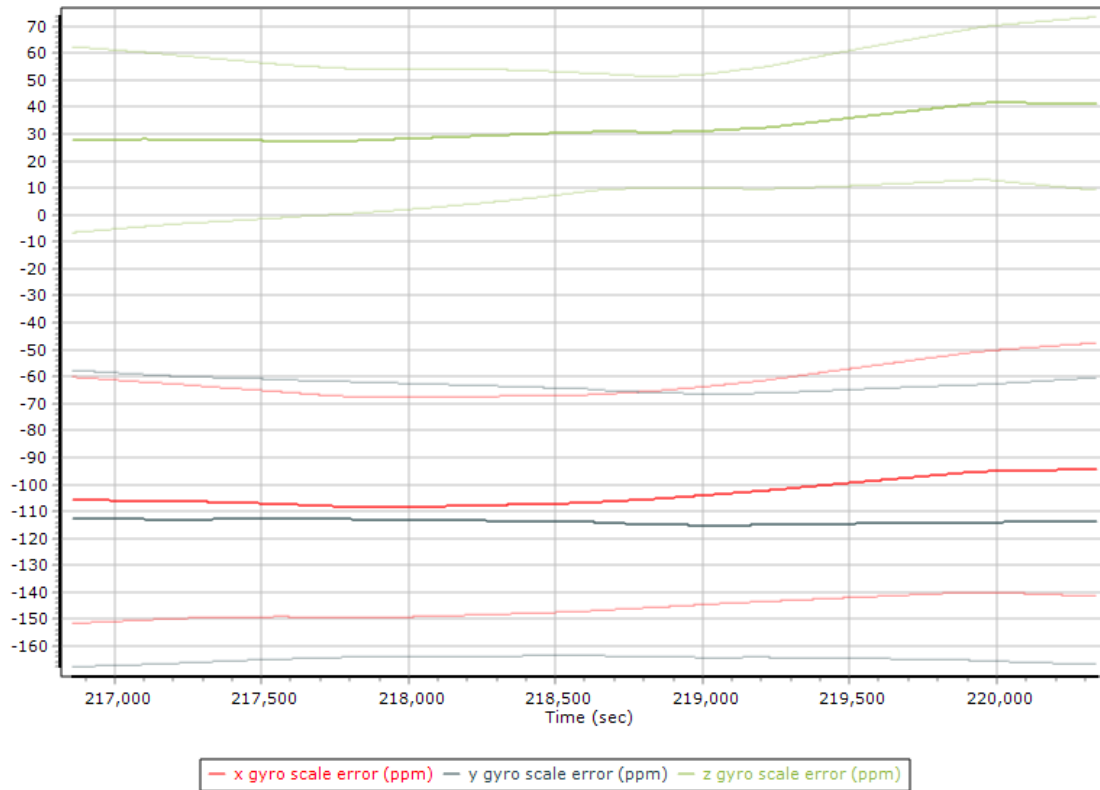
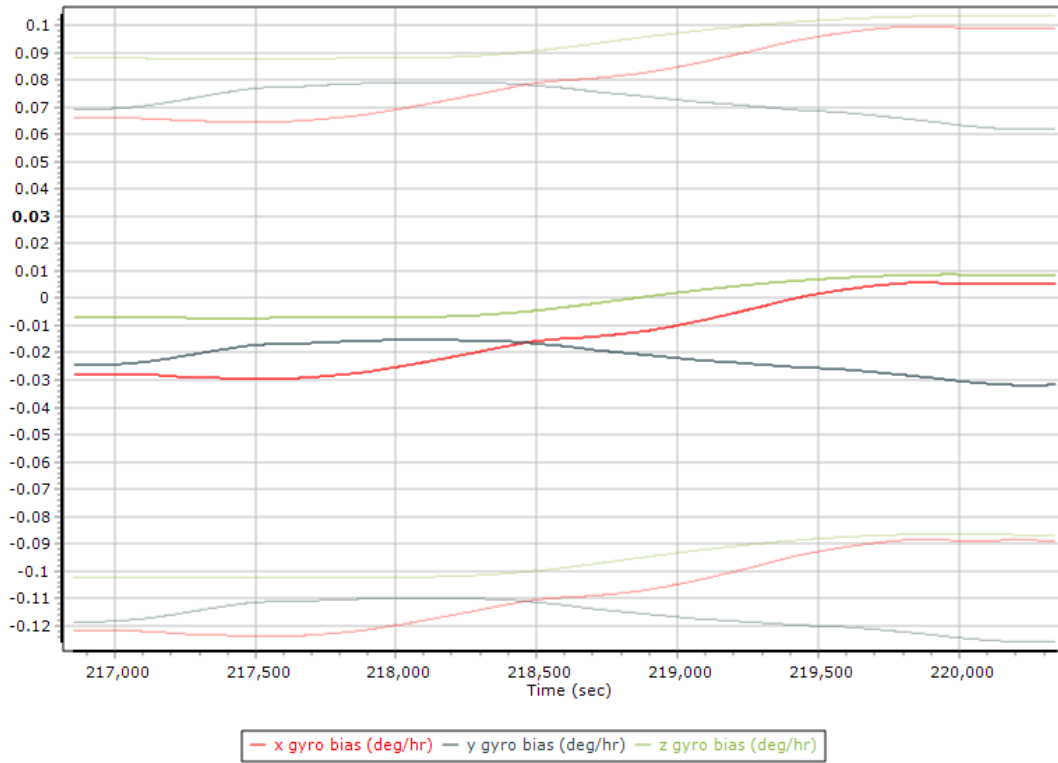
Sensor Errors



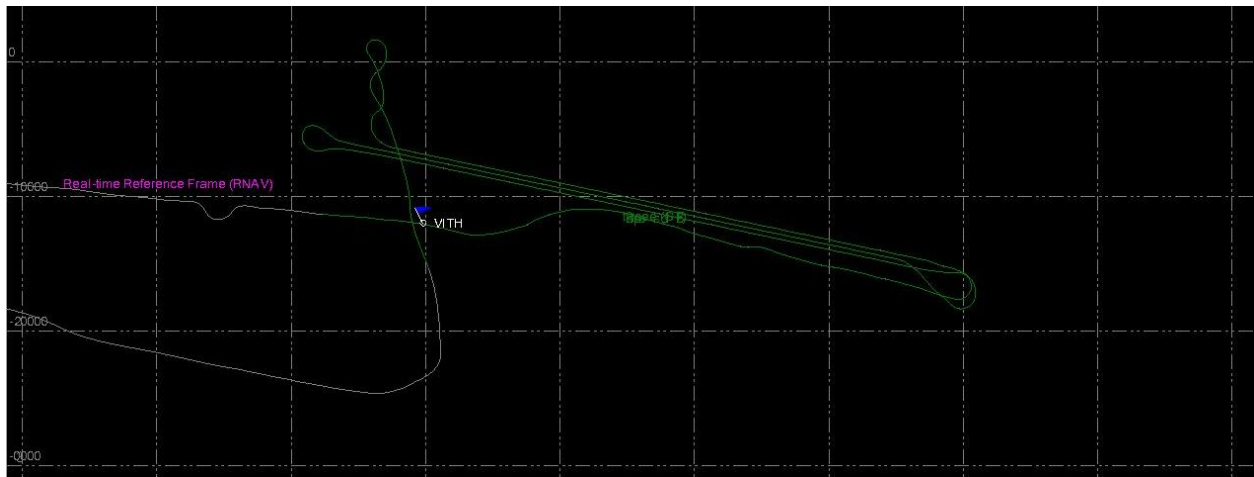
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



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Project Settings

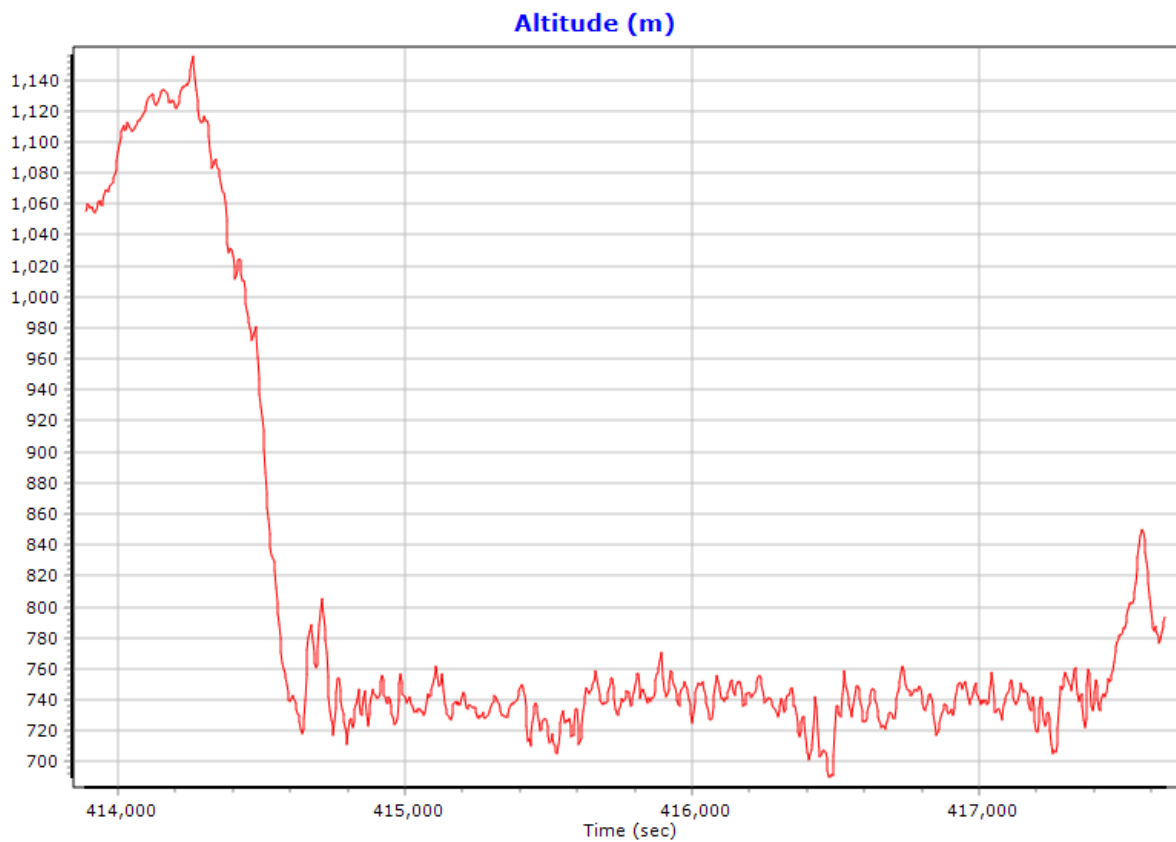
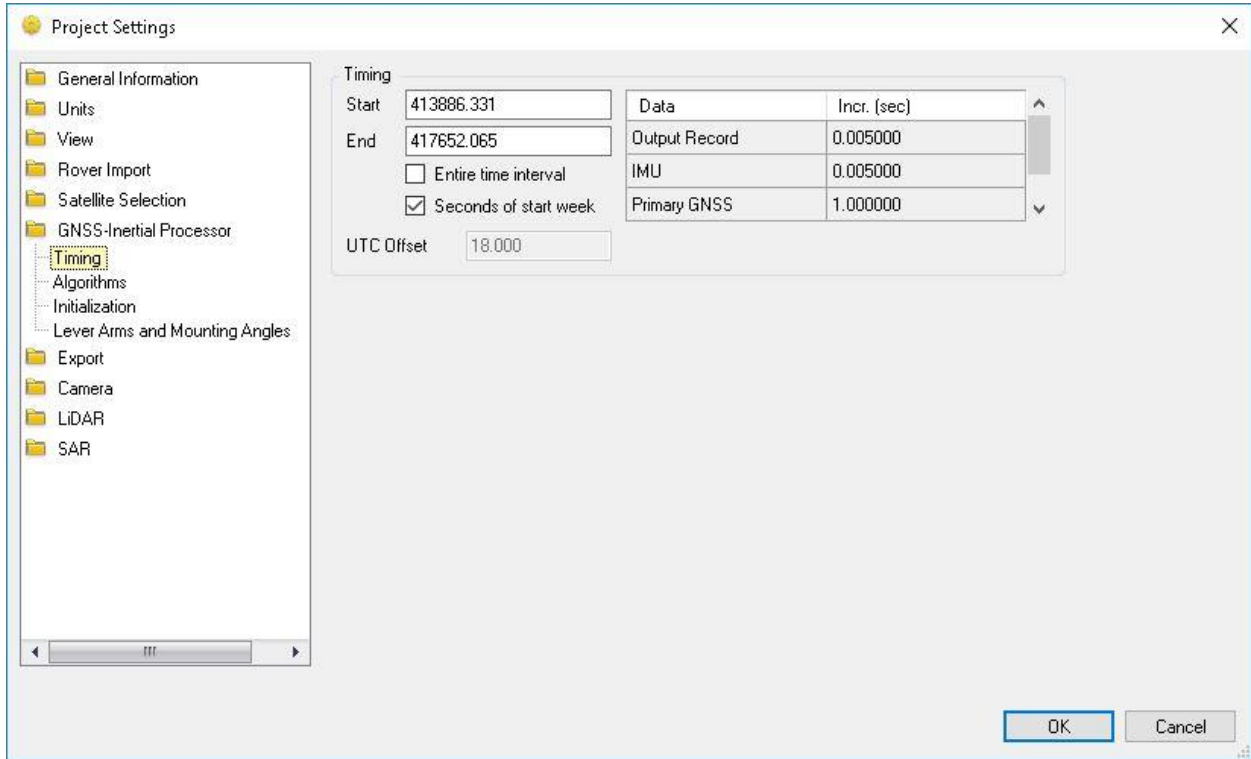
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LIDAR
- SAR

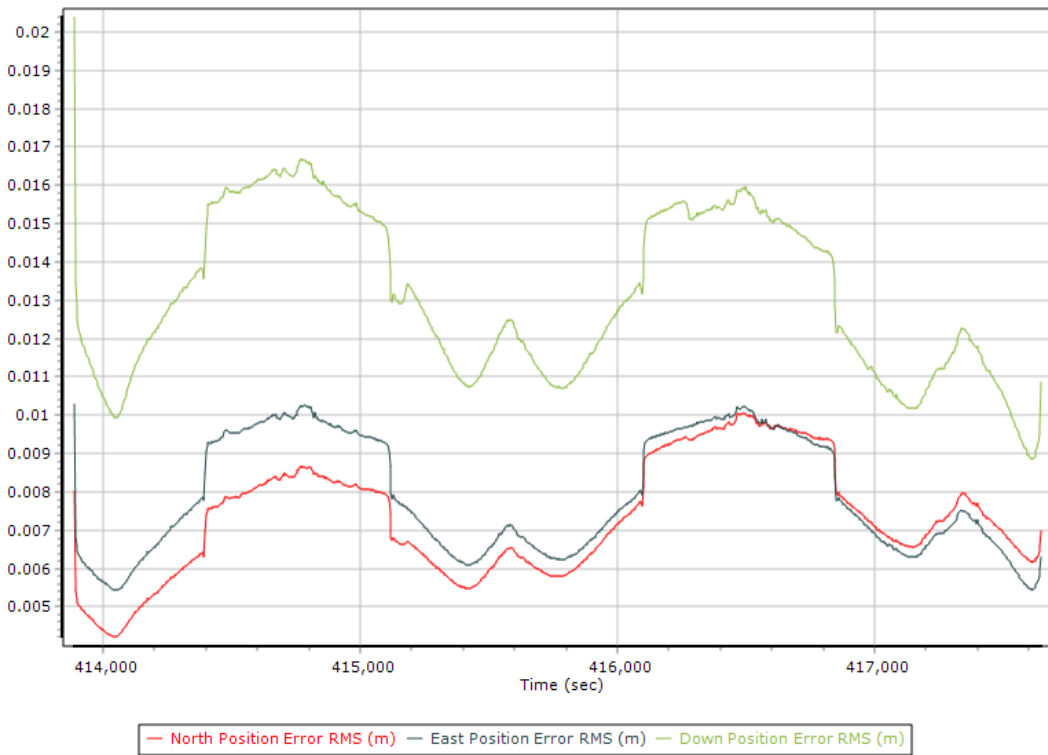
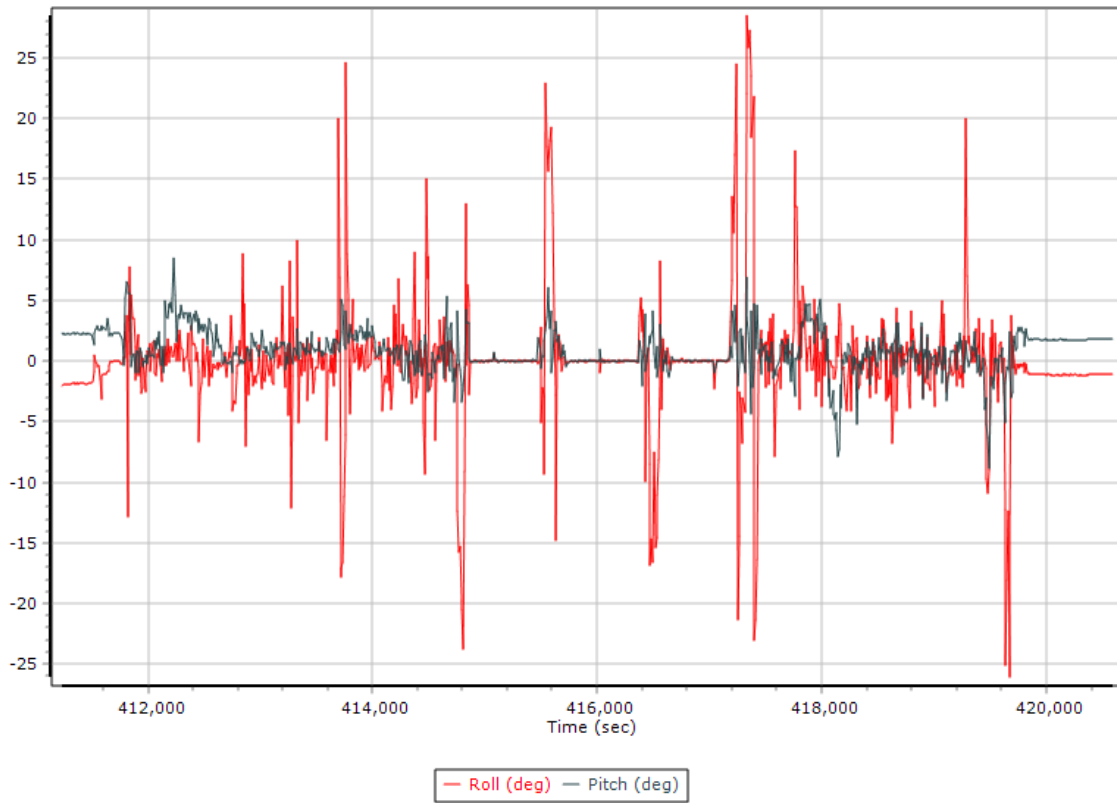
Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.049 m	0.003 m	-1.230 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

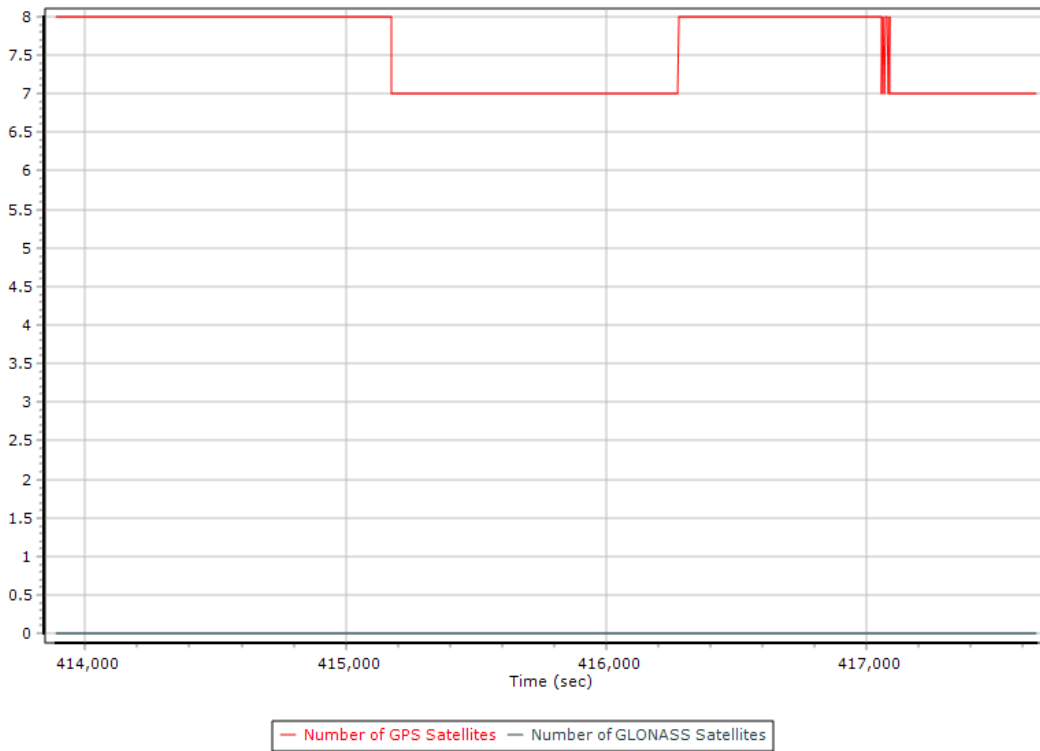
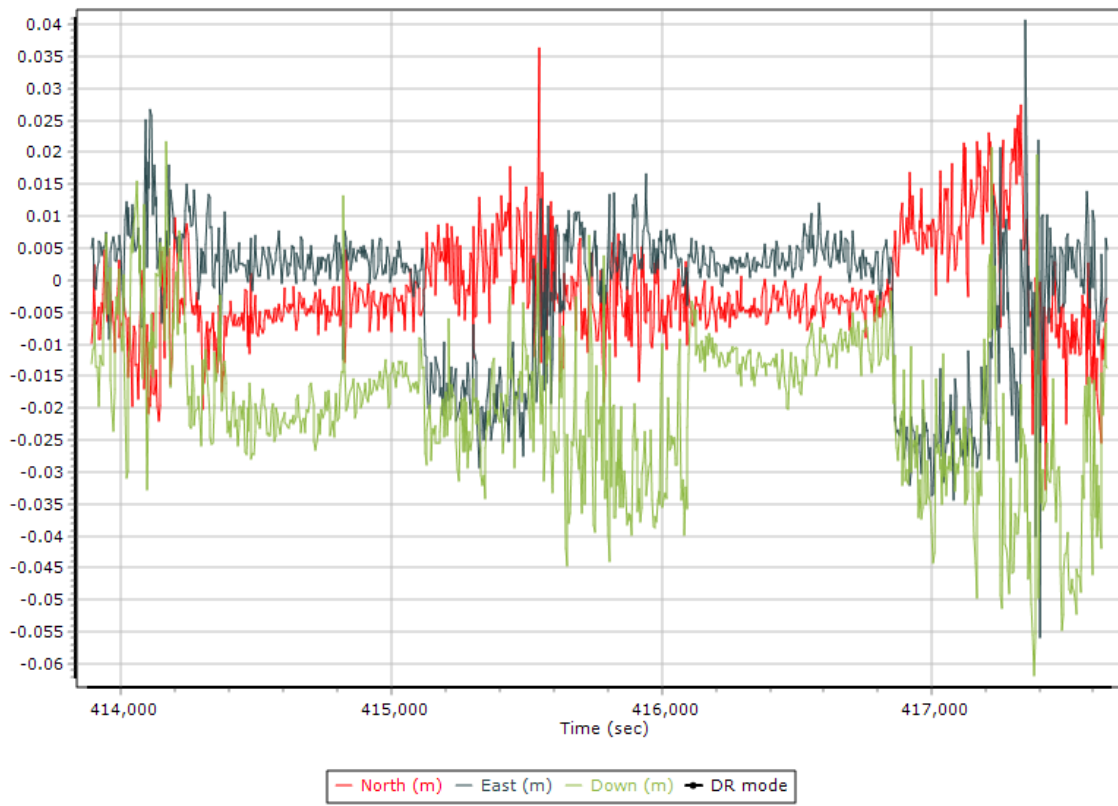
Standard Deviation: <3cm 10cm 50cm 1m 10m

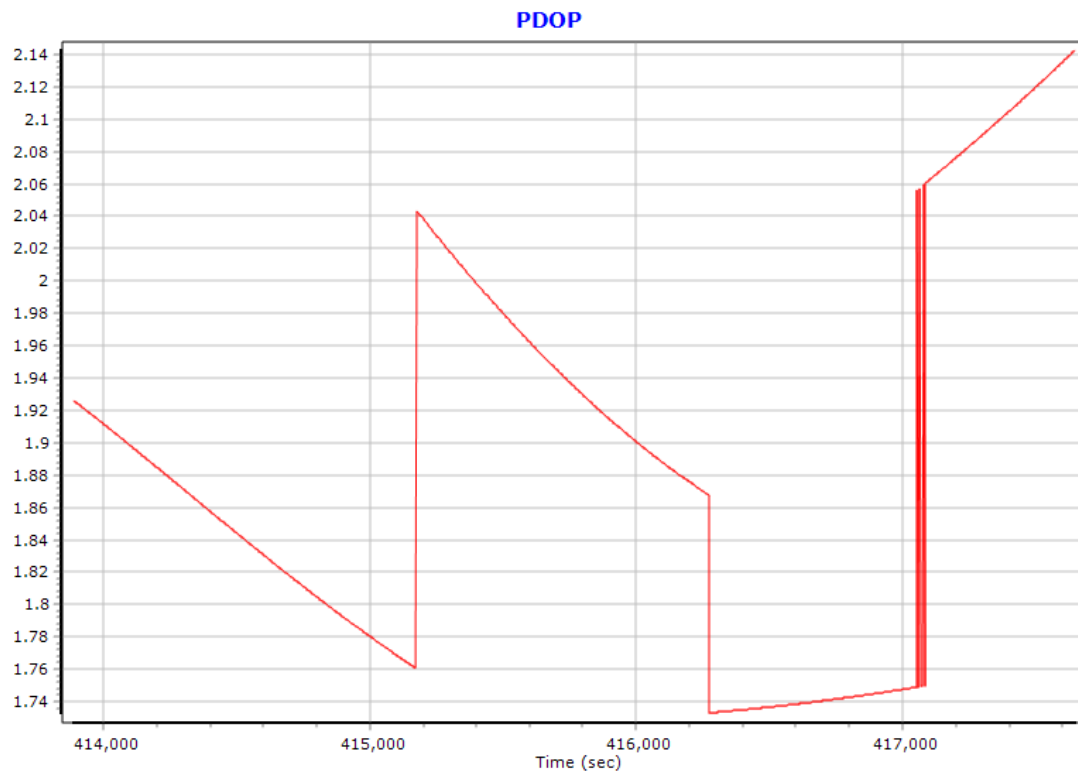
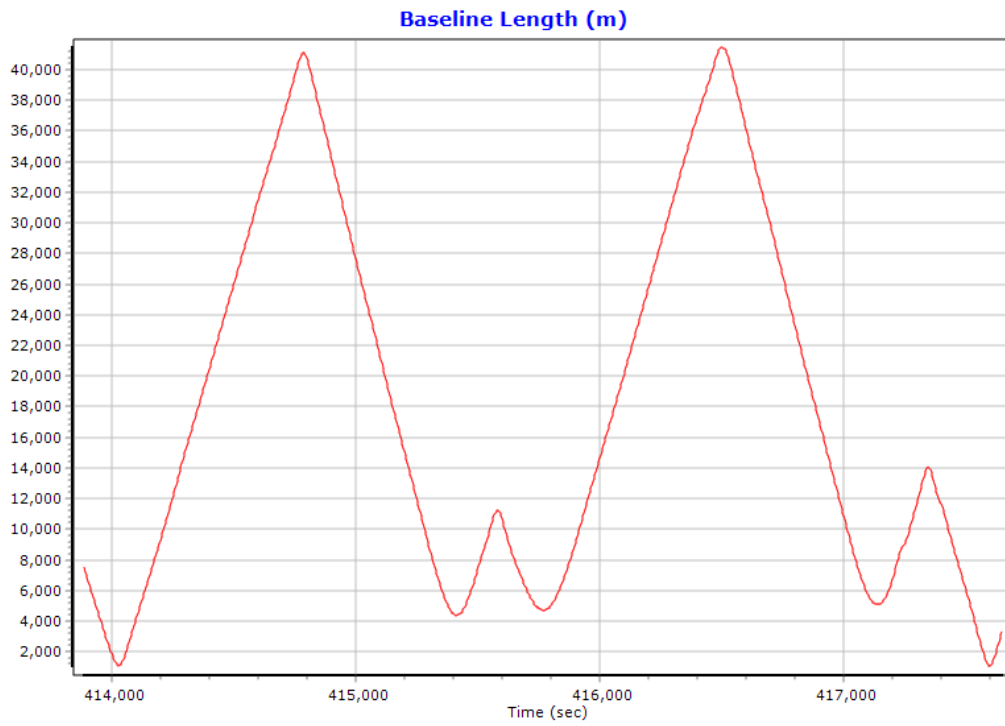
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

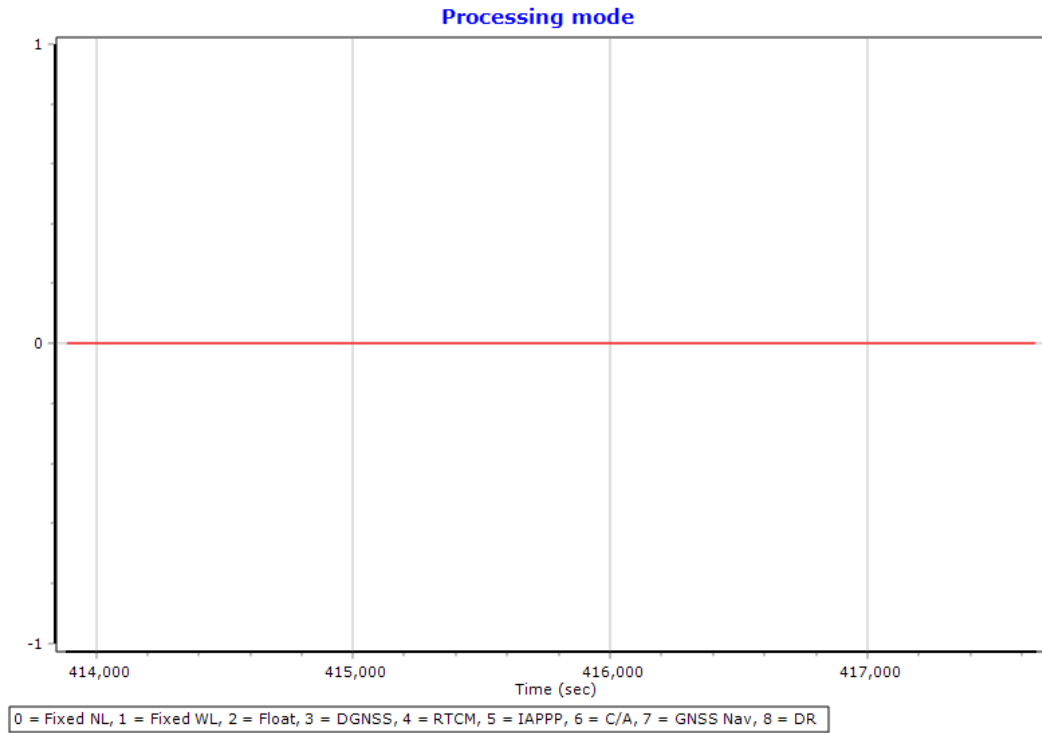
OK Cancel



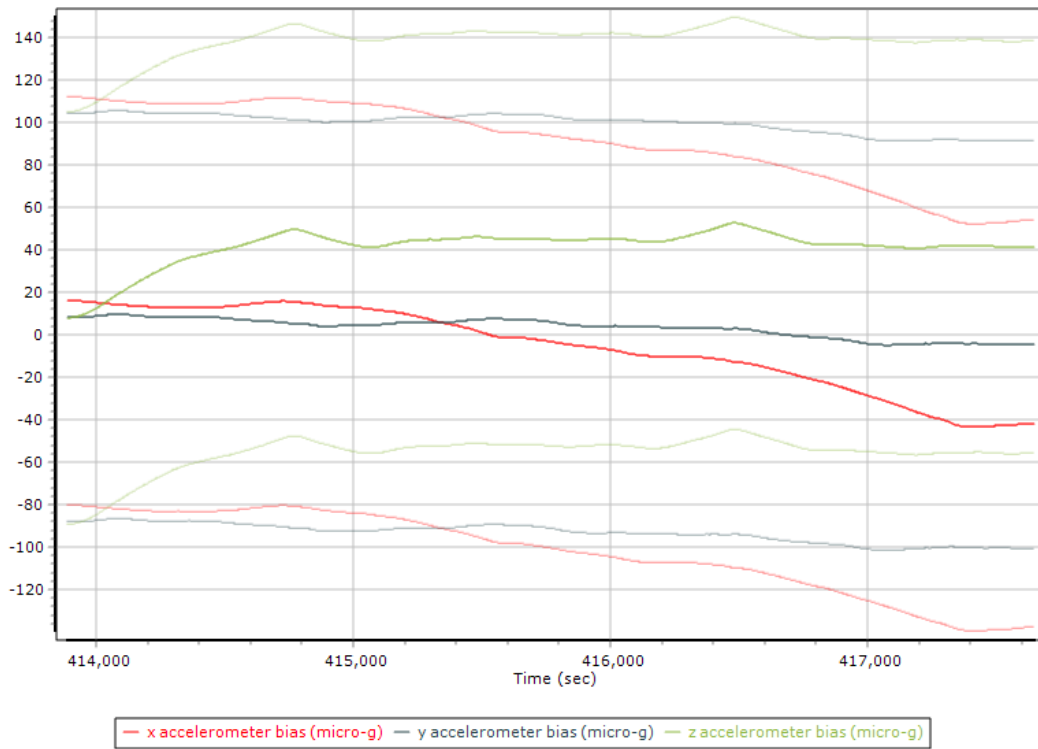


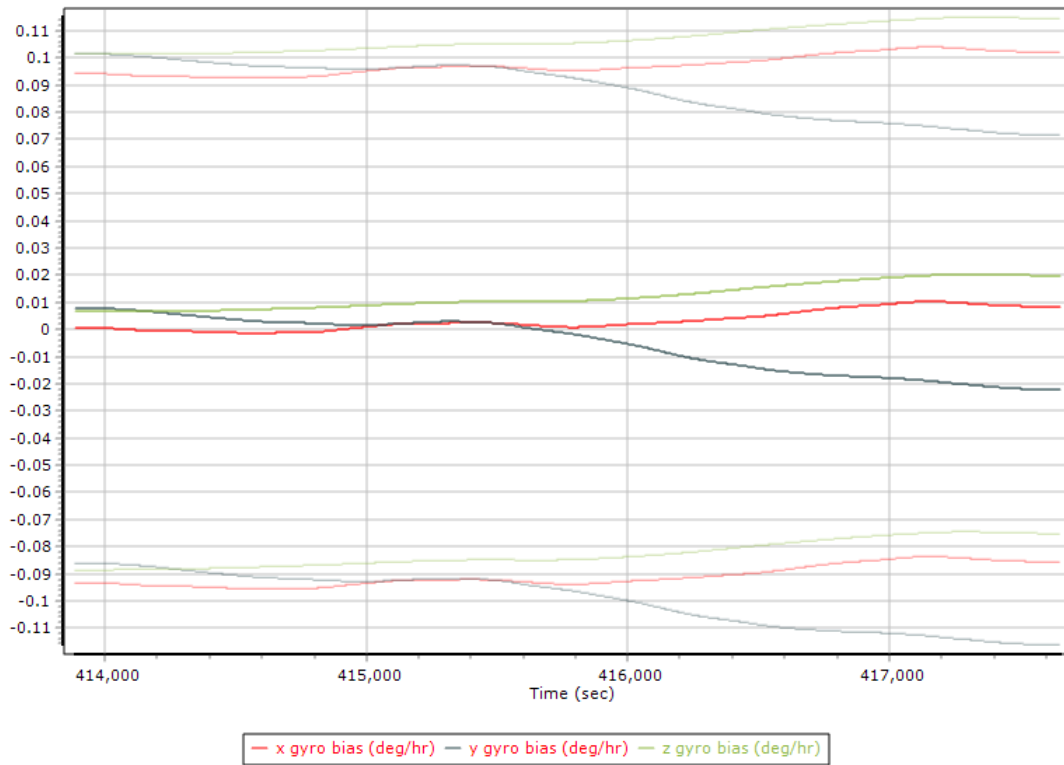
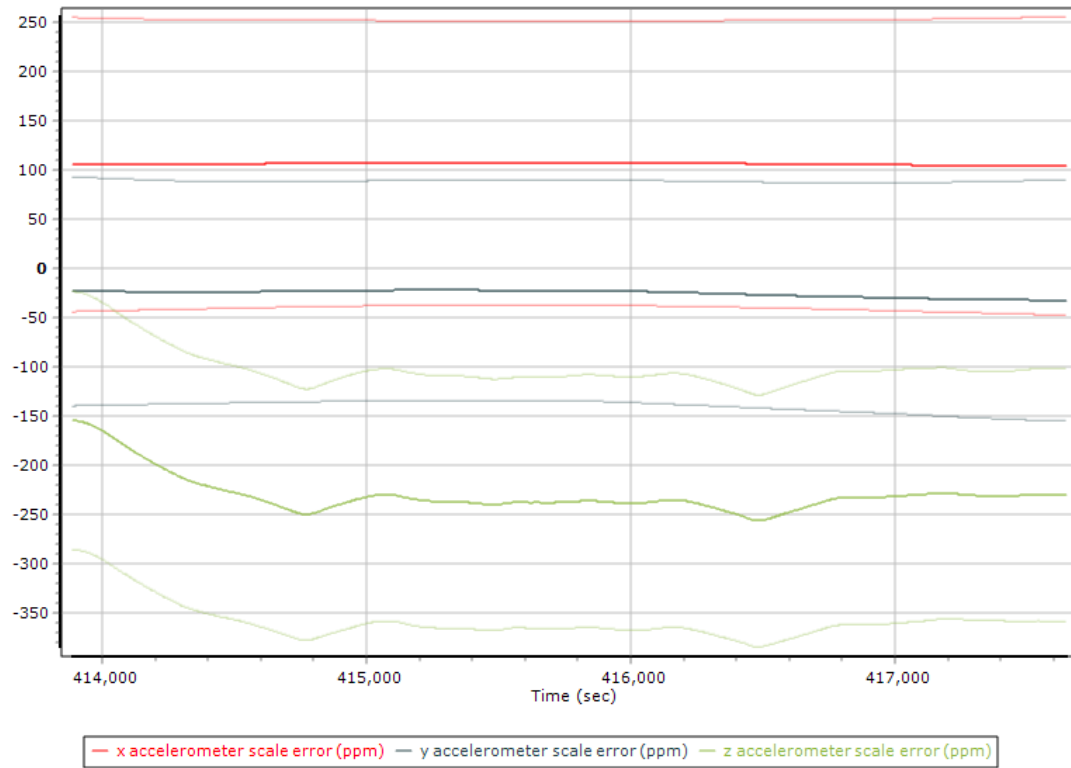


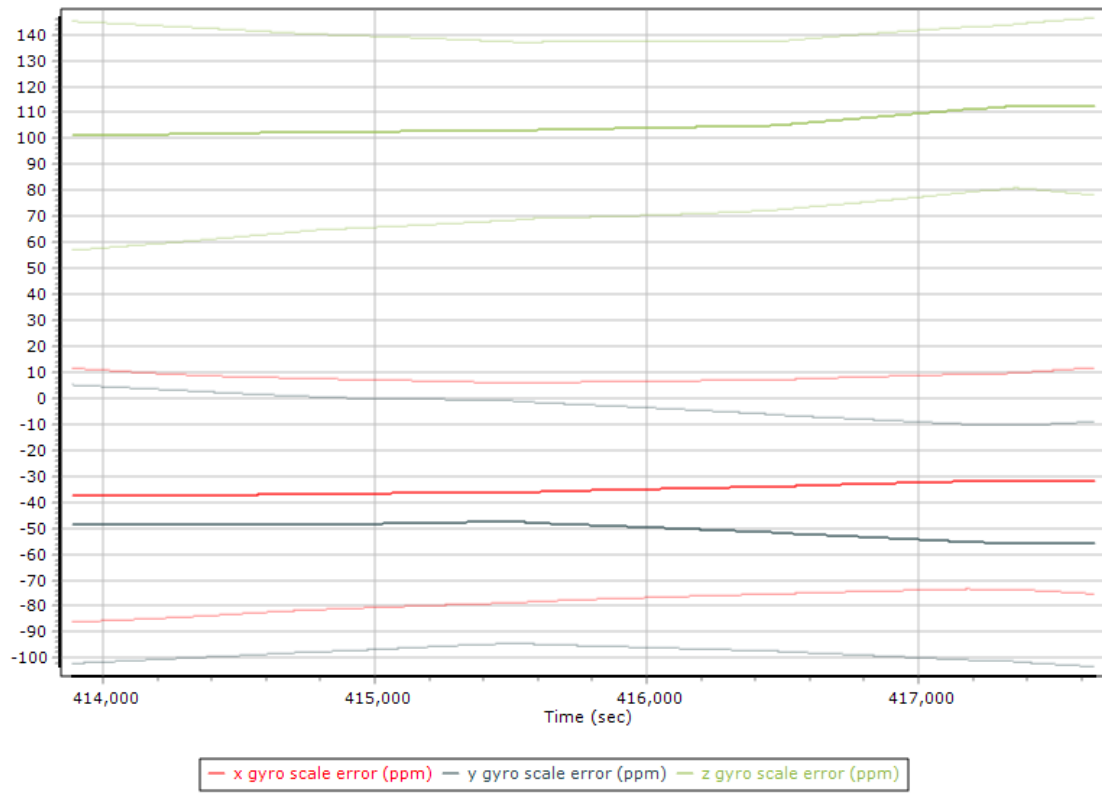




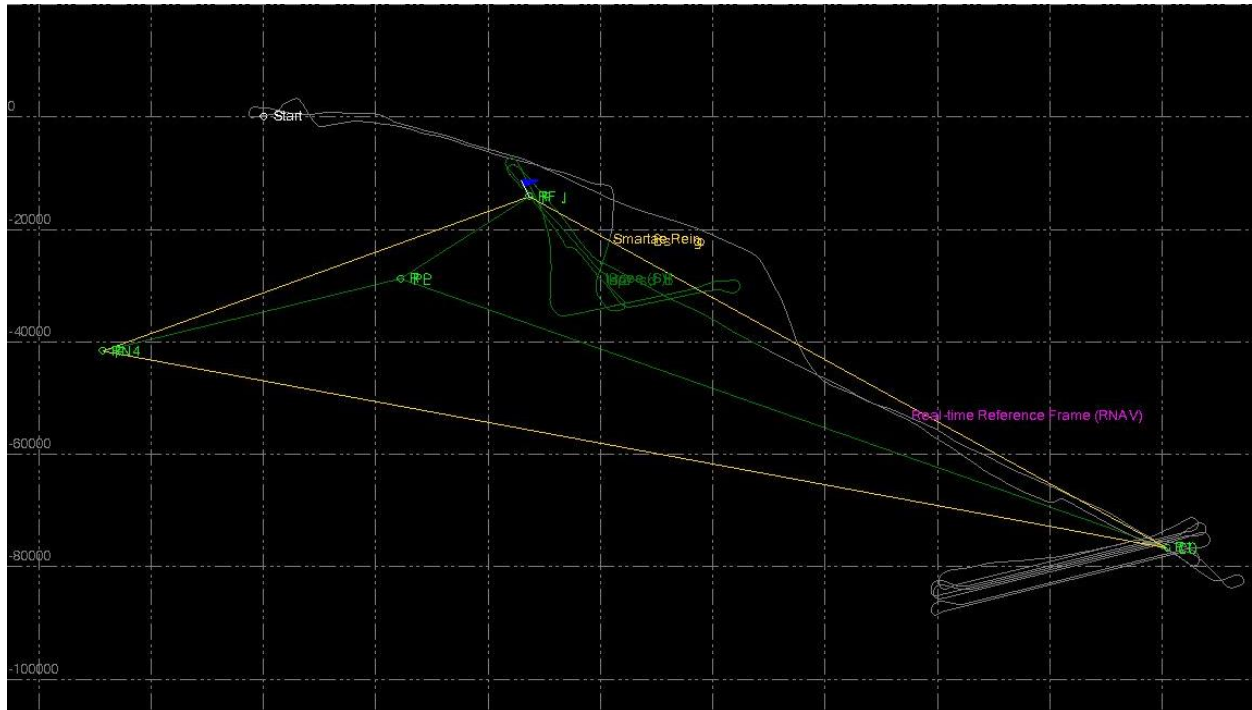
Sensor Errors

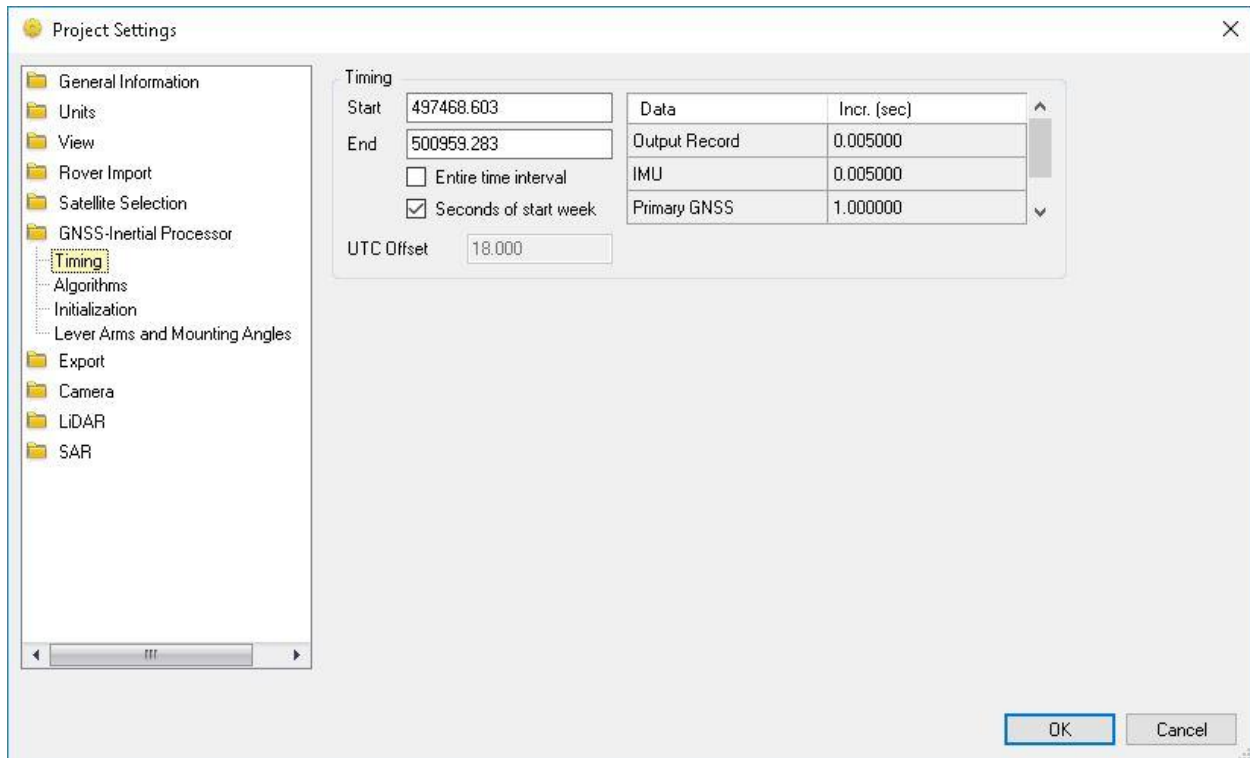
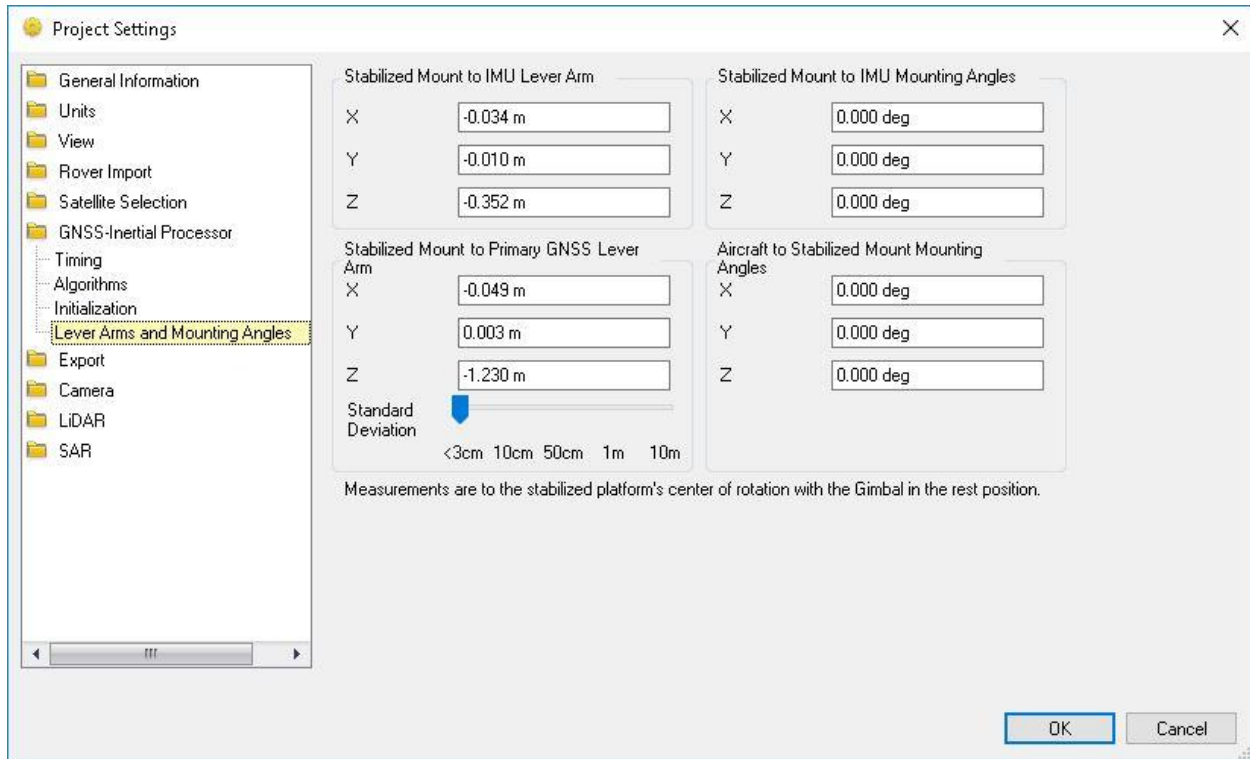


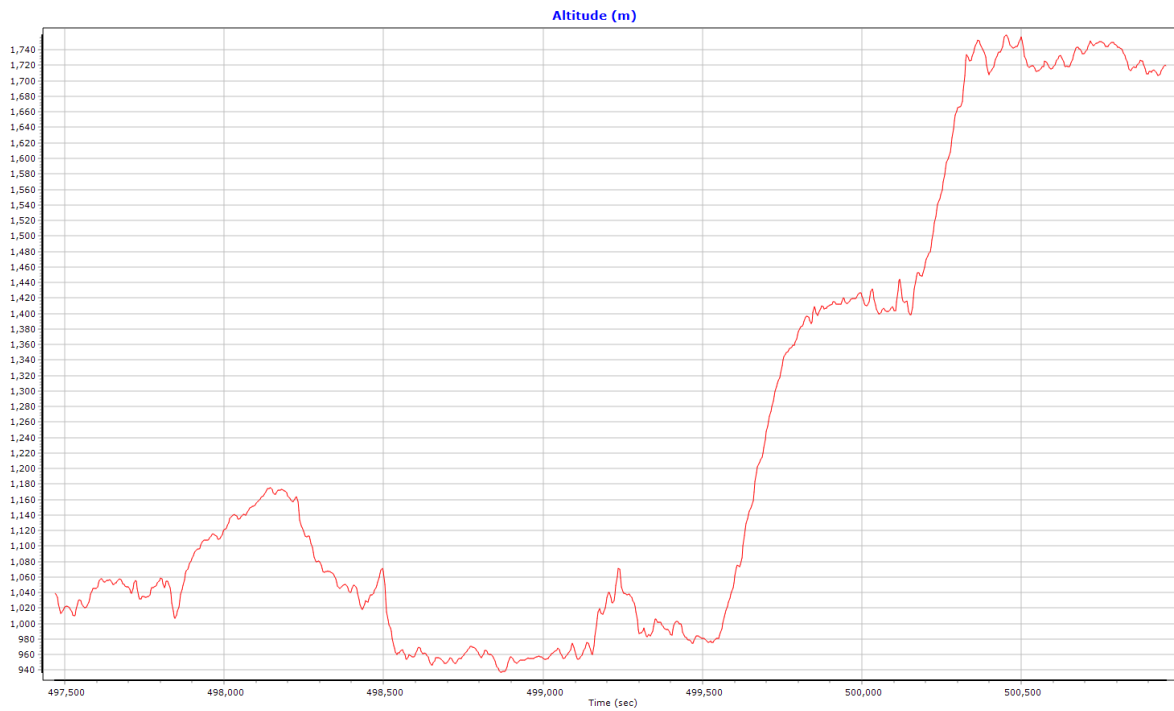


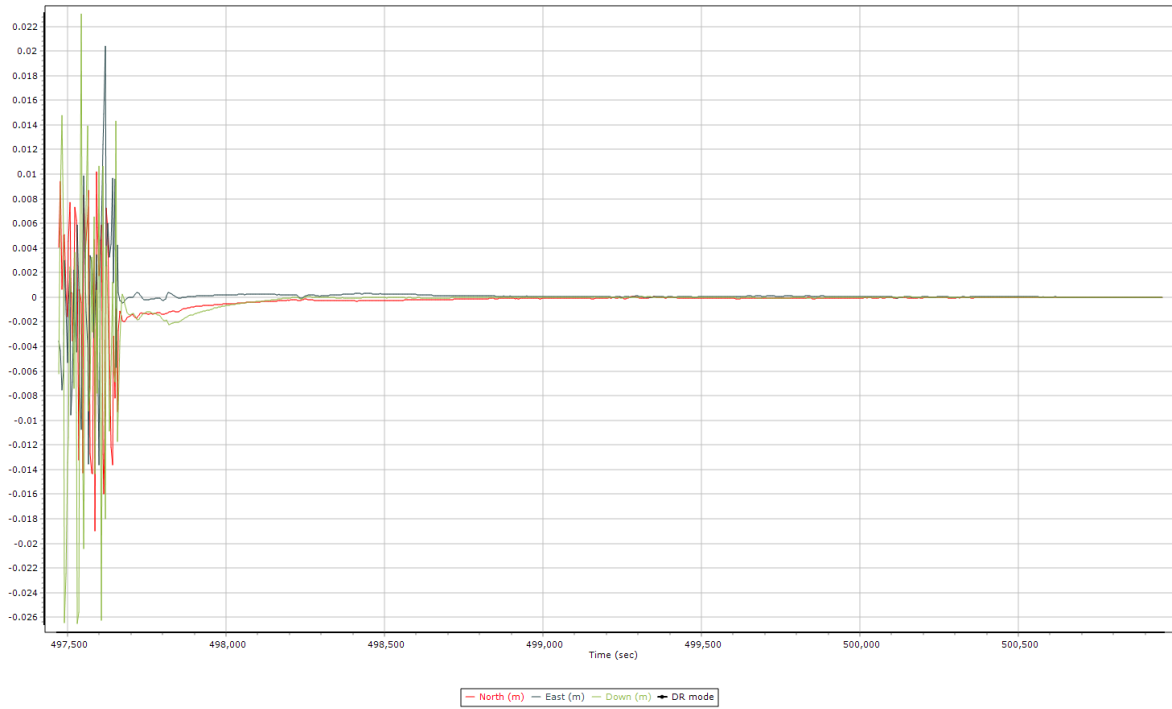
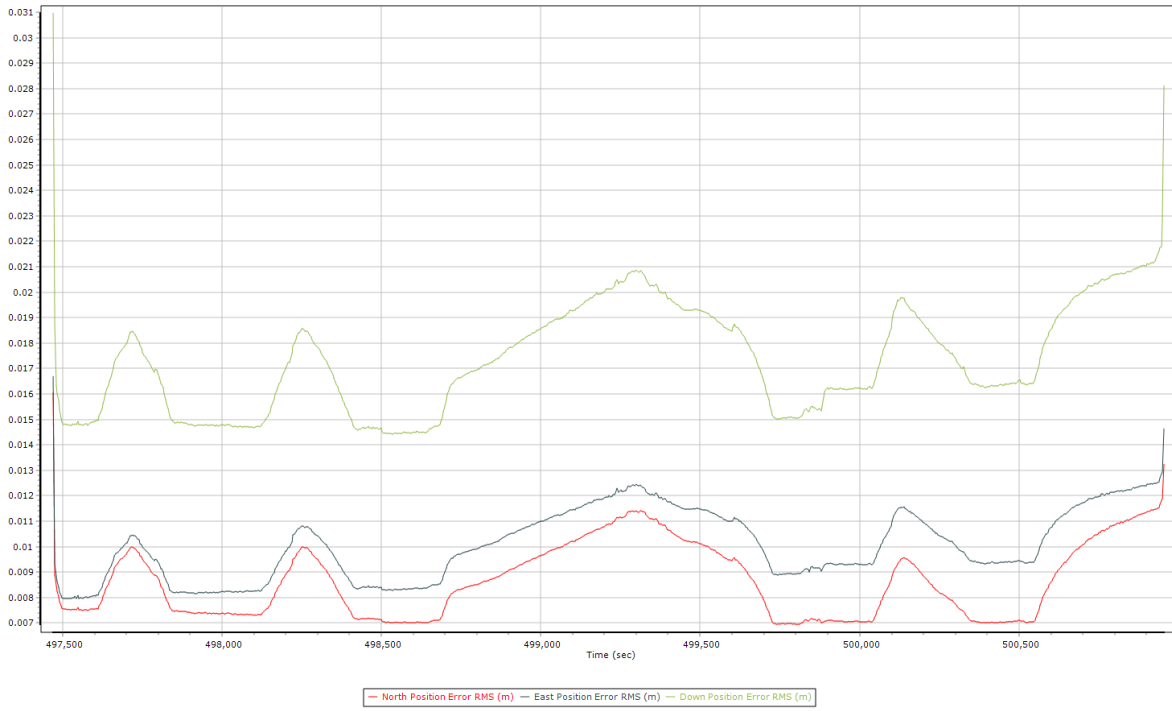


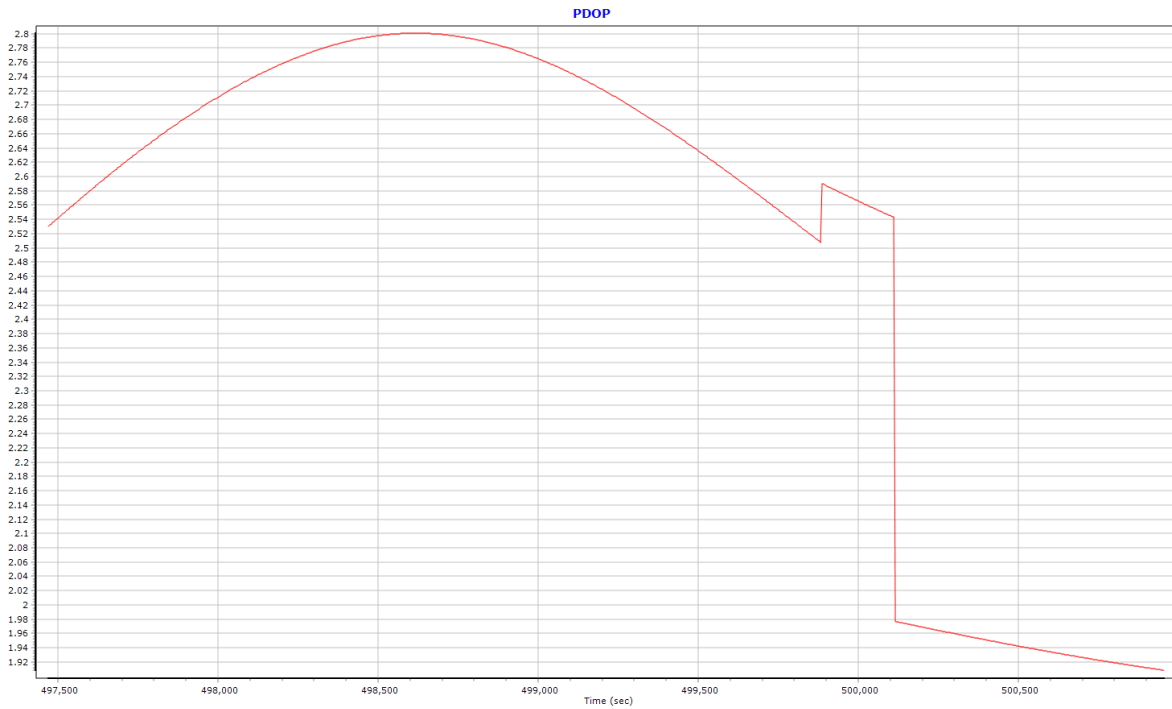
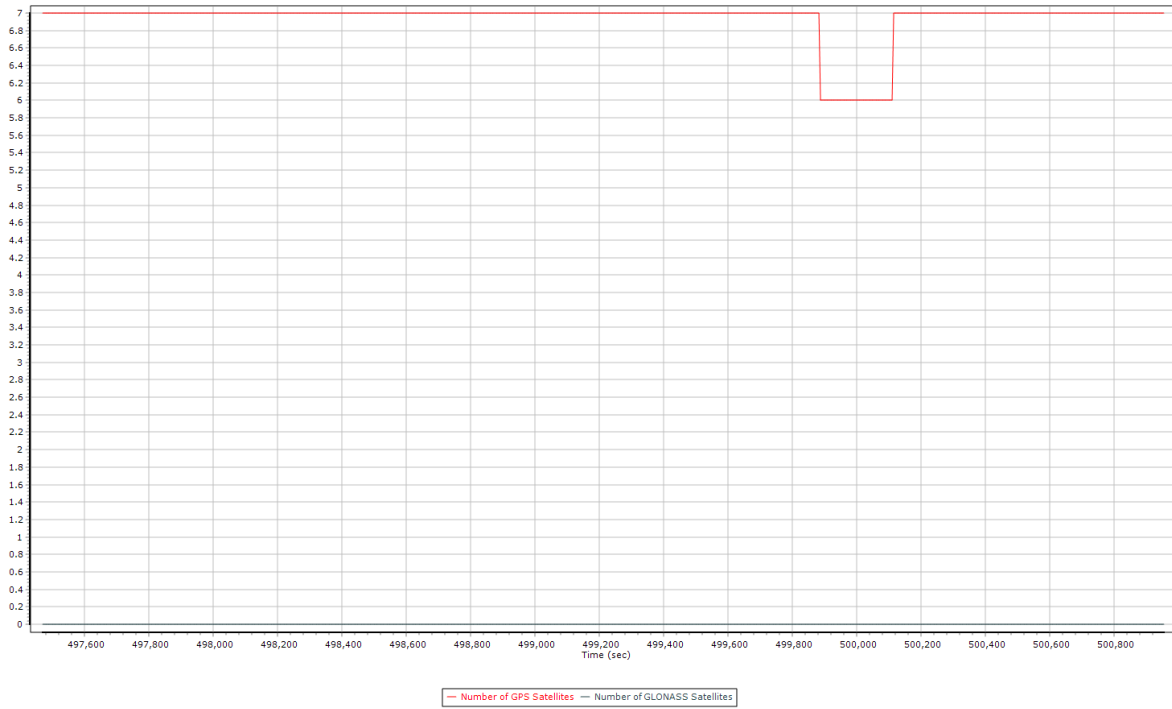
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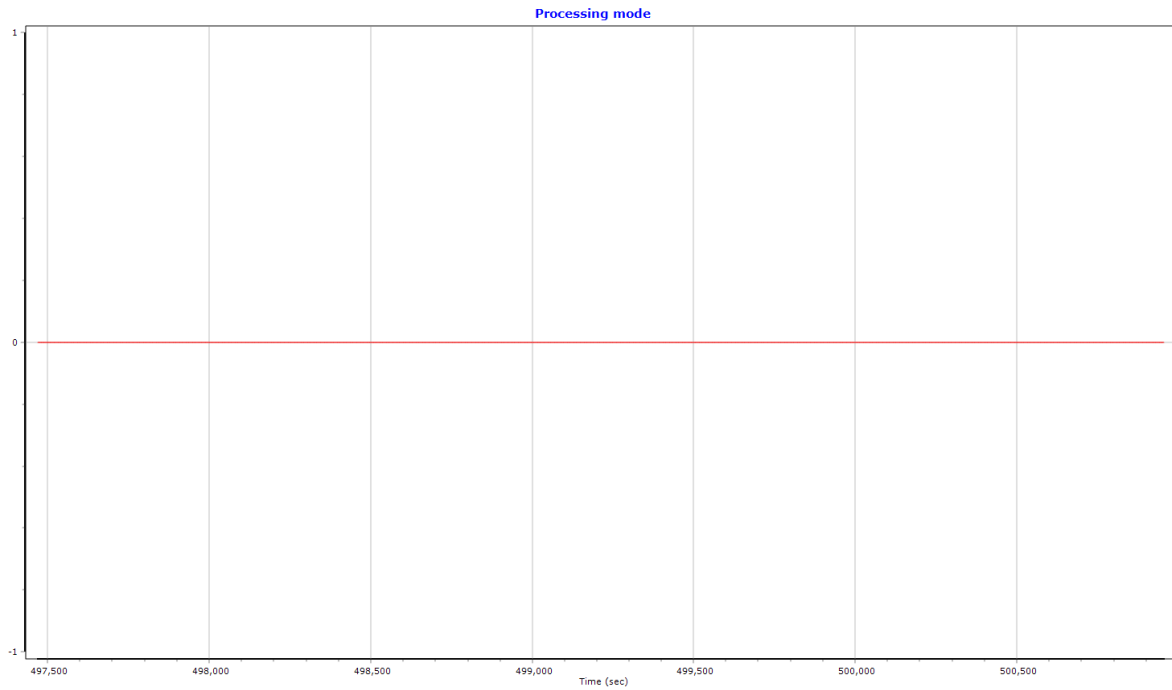




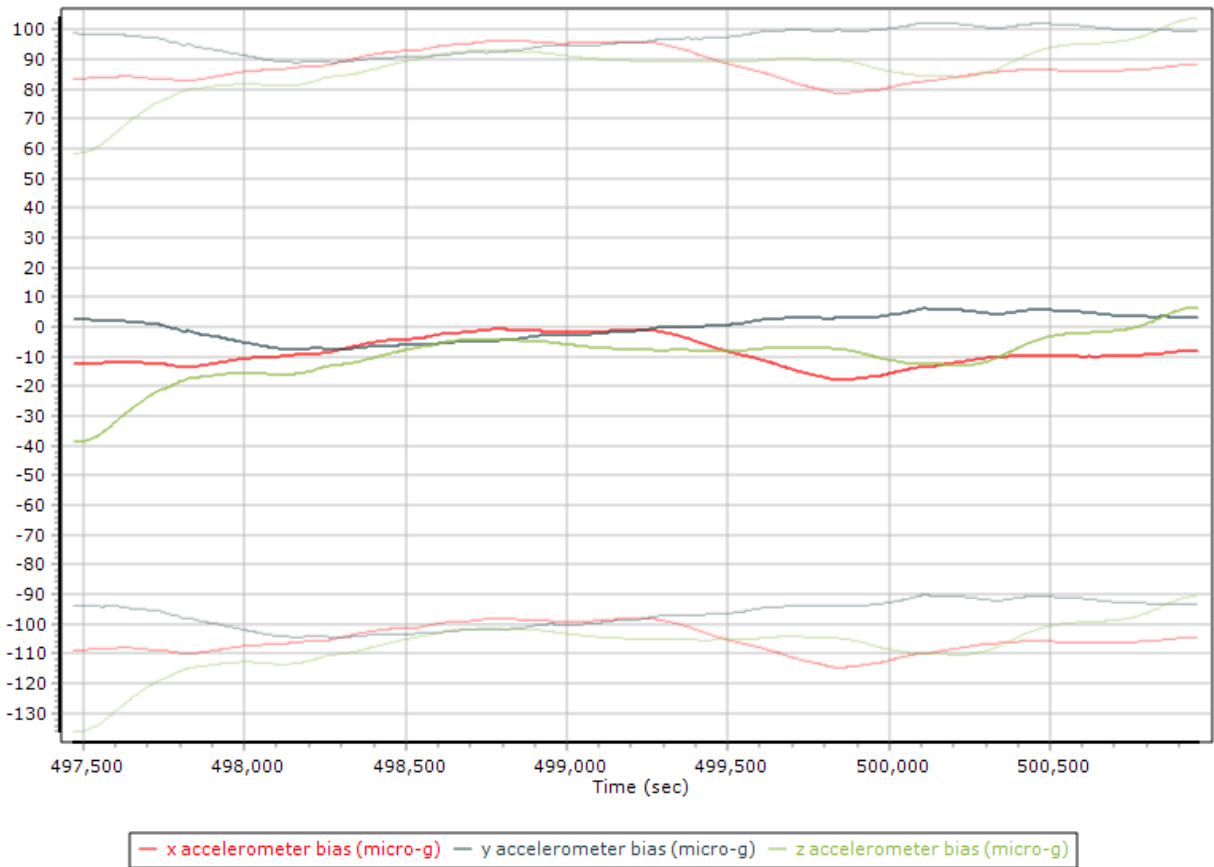


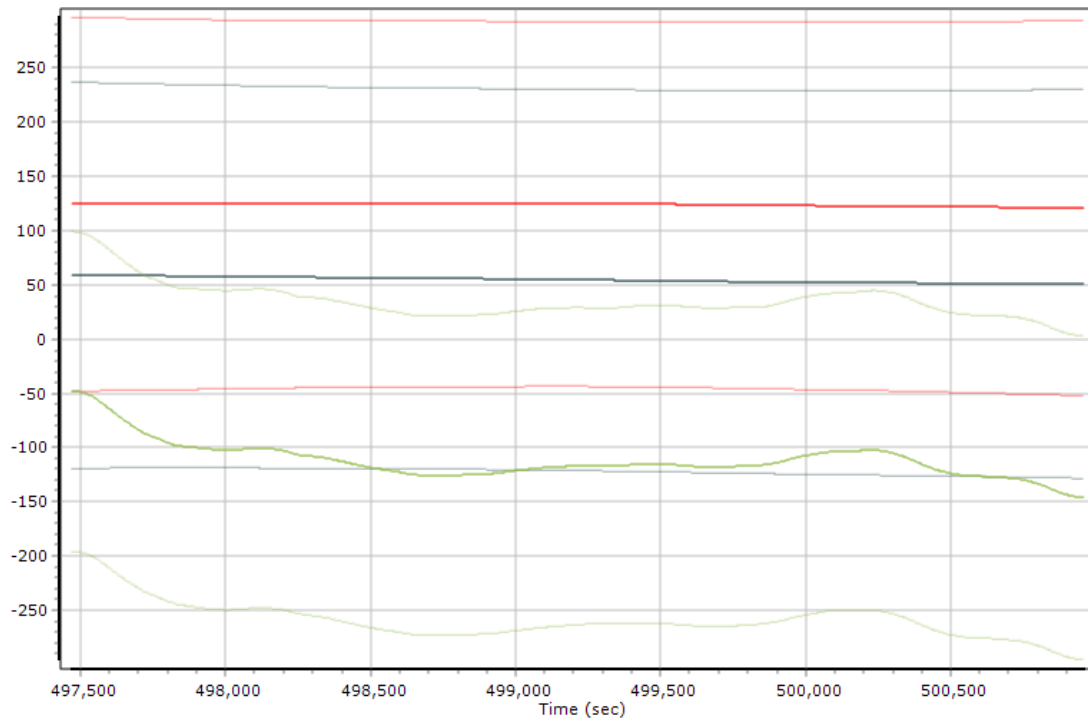




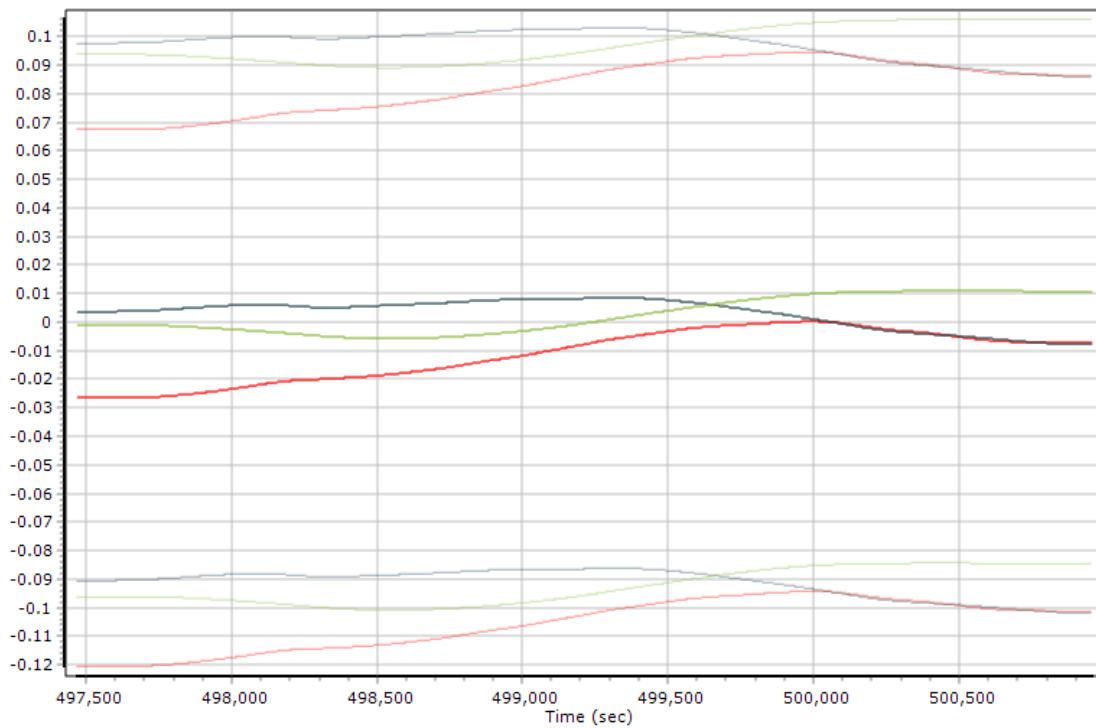


Sensor Errors

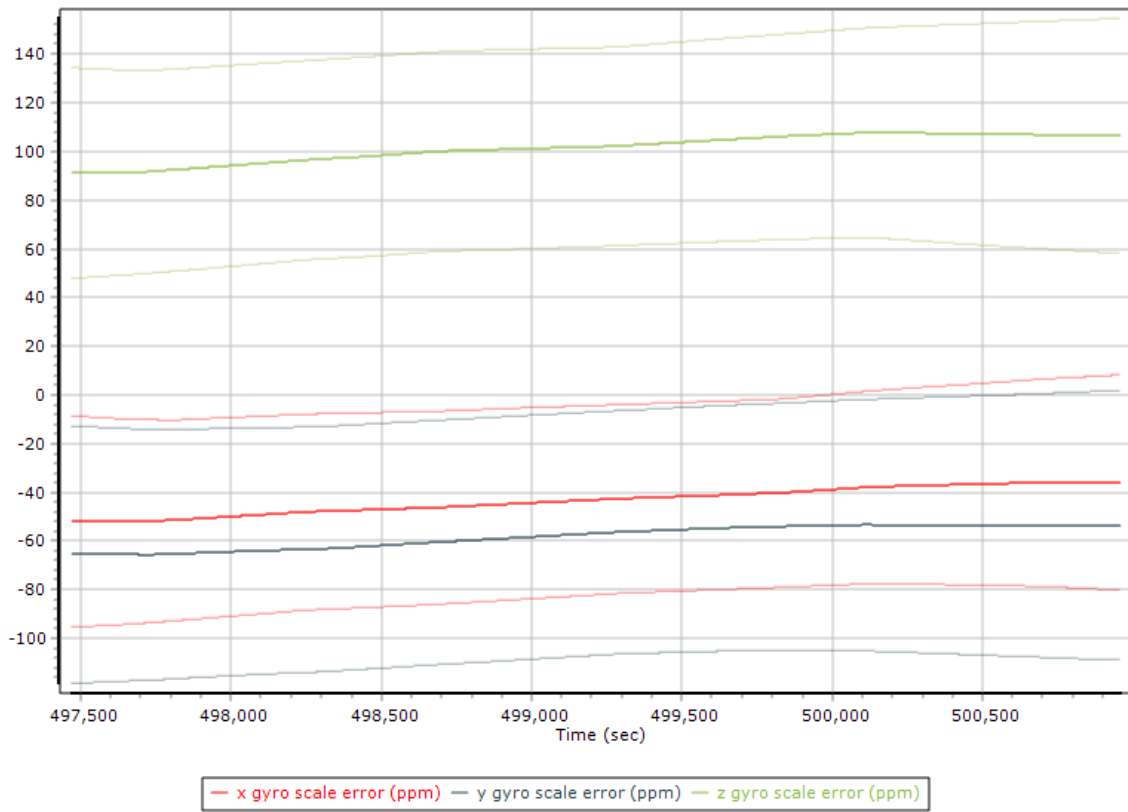




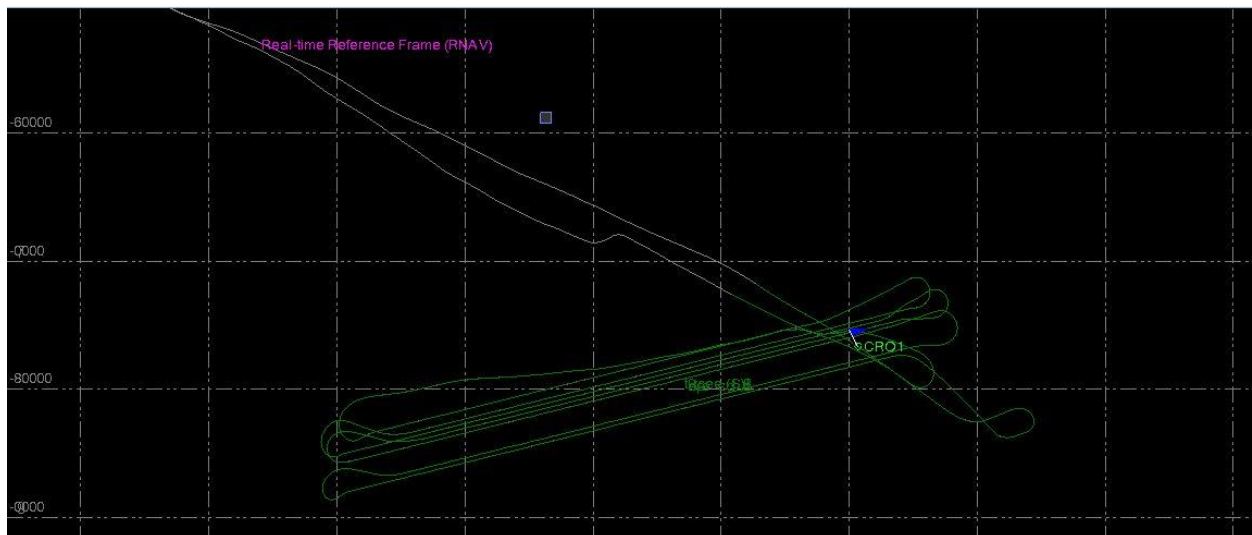
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

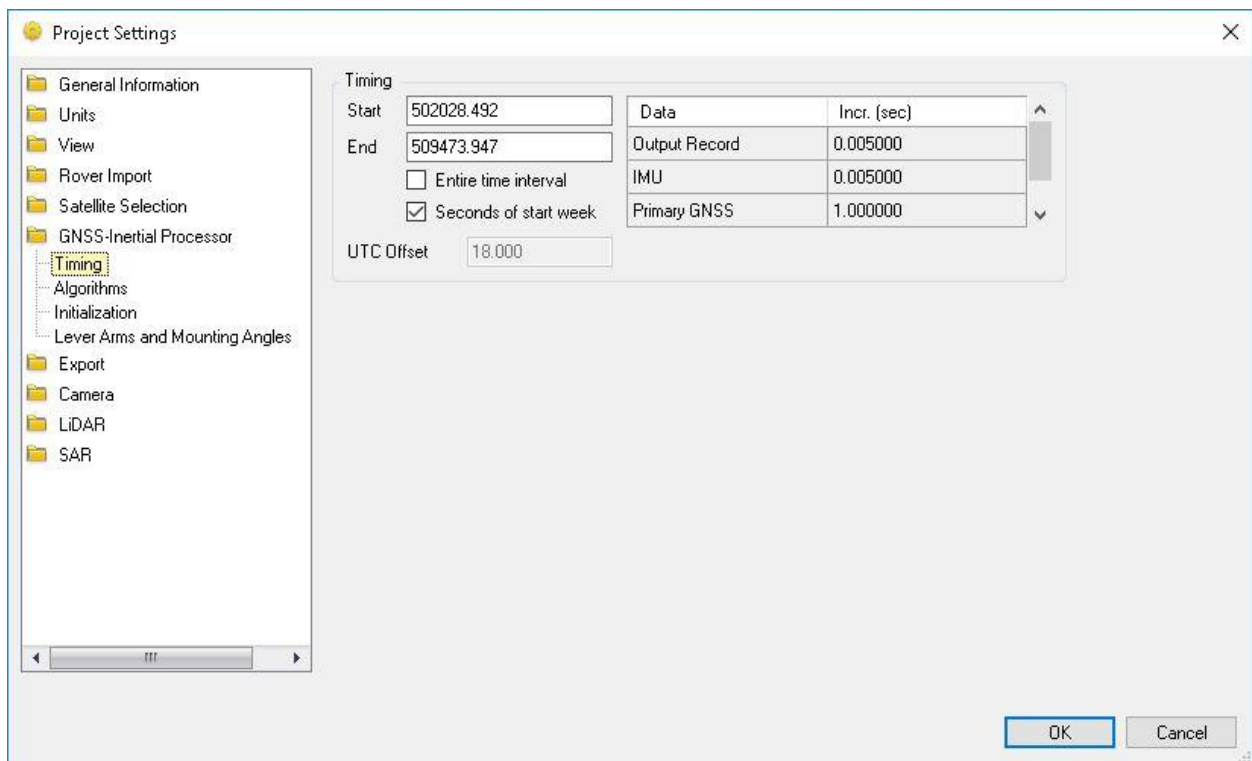
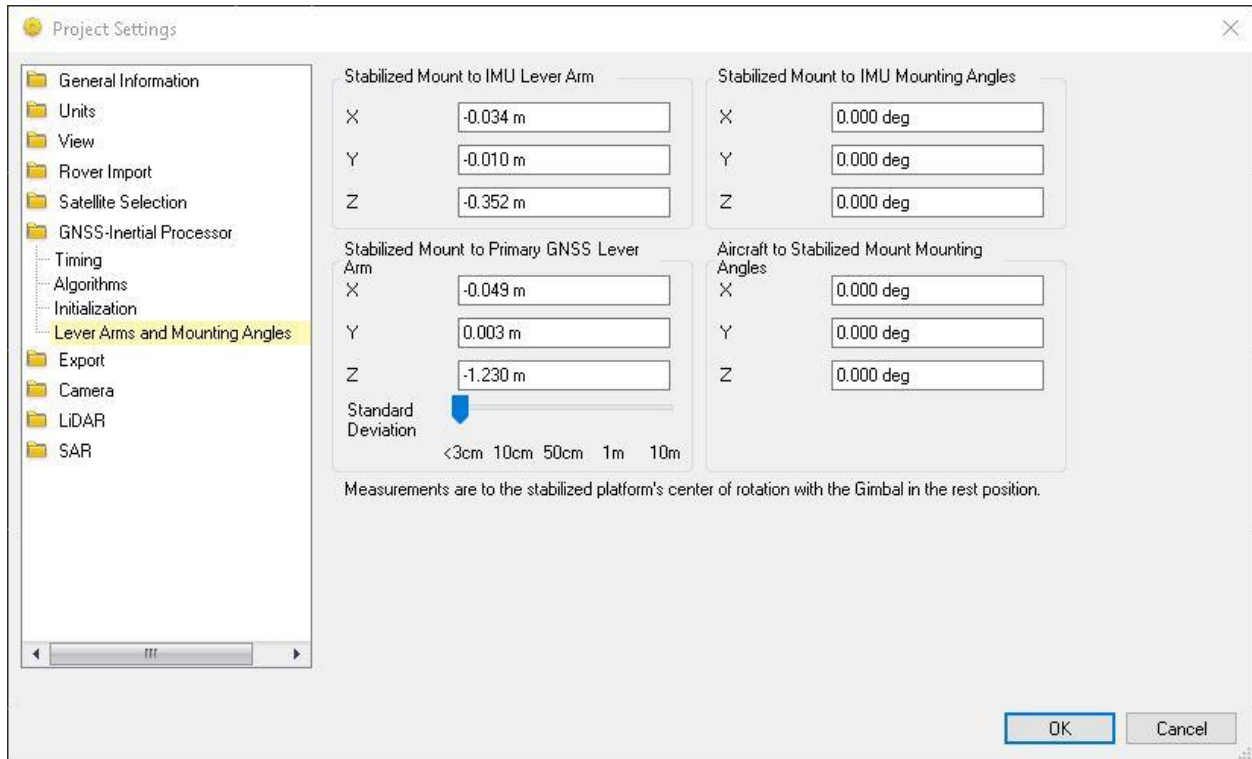


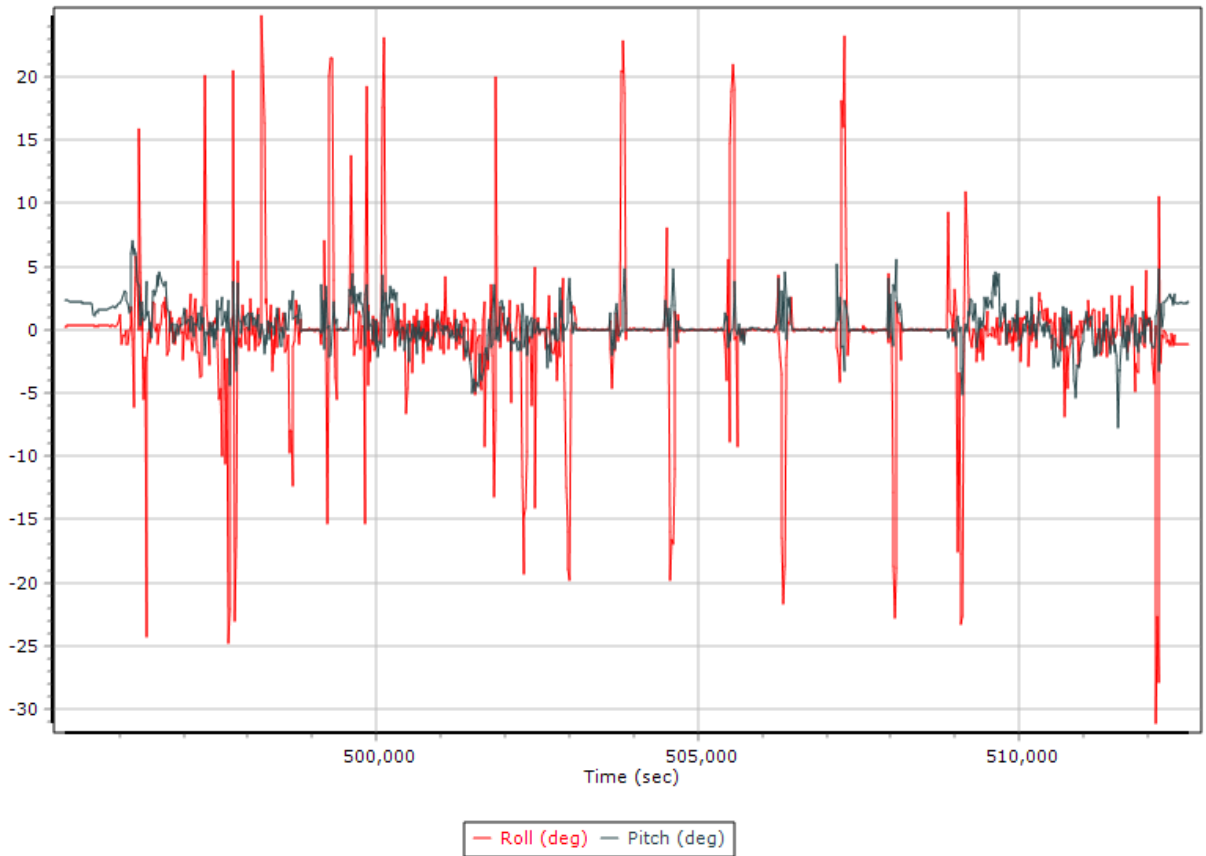
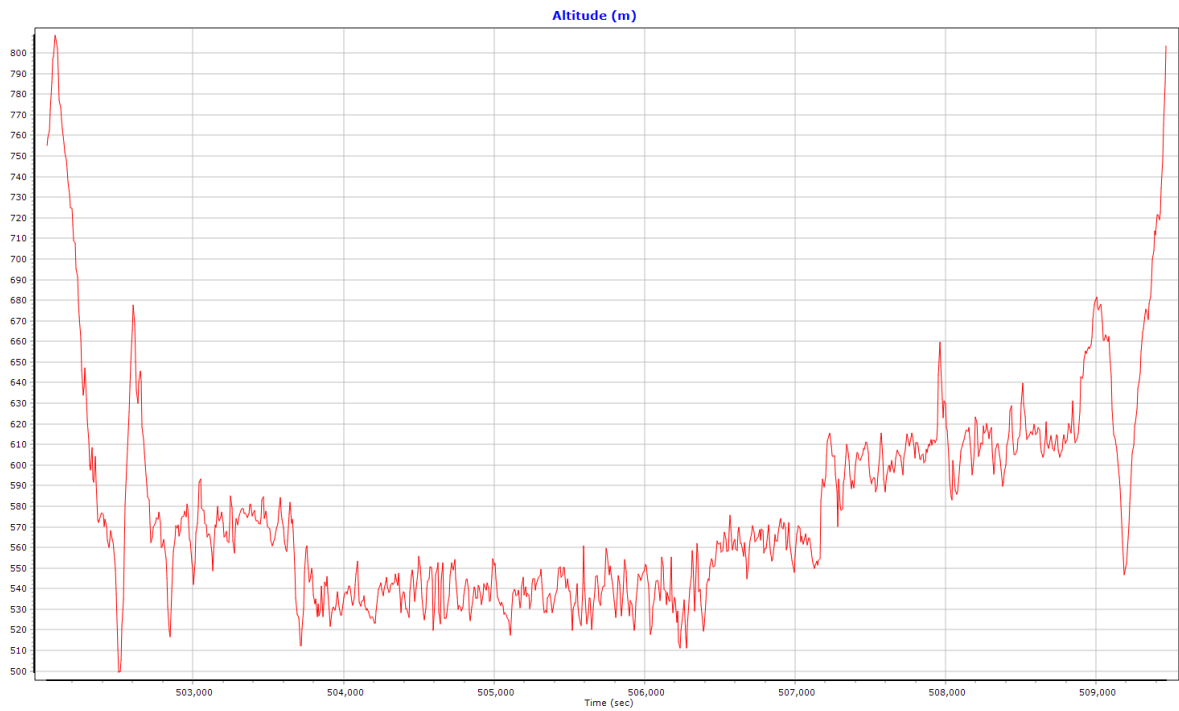
— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

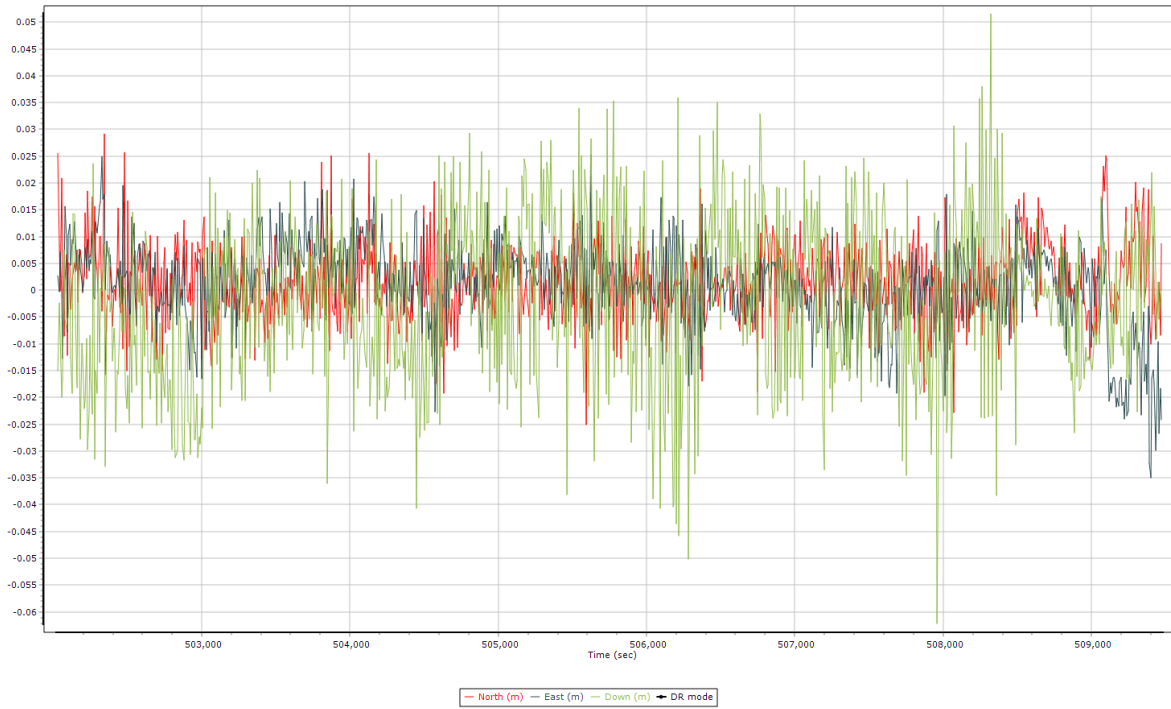
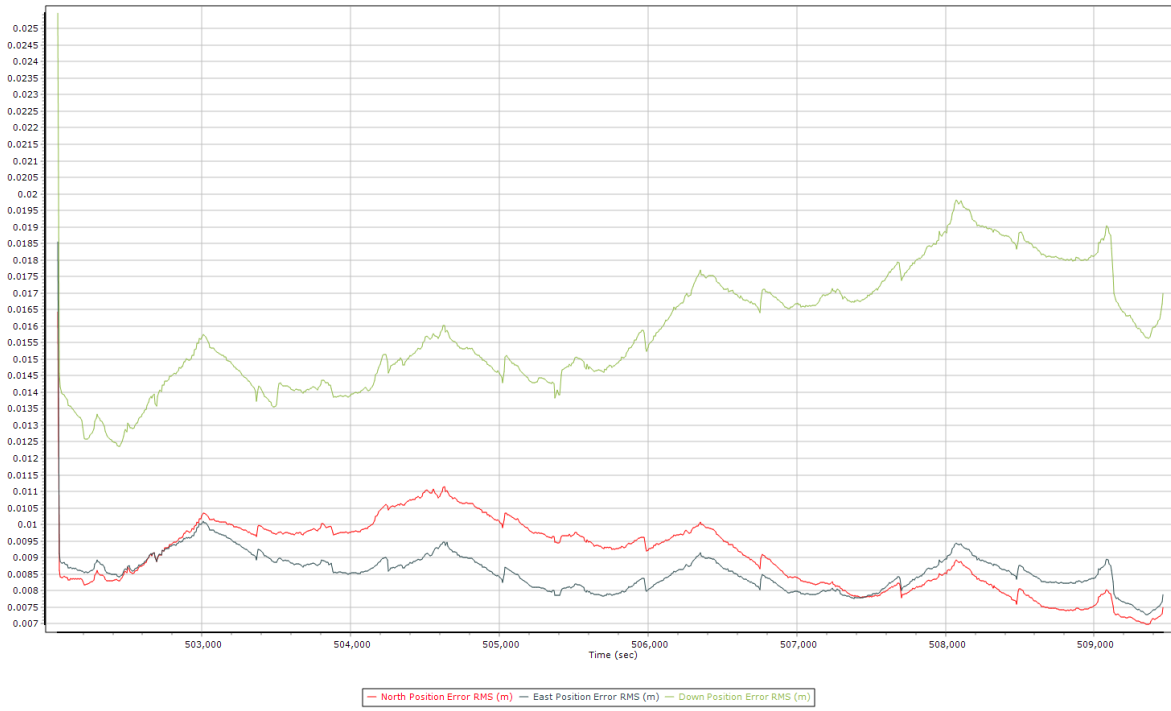


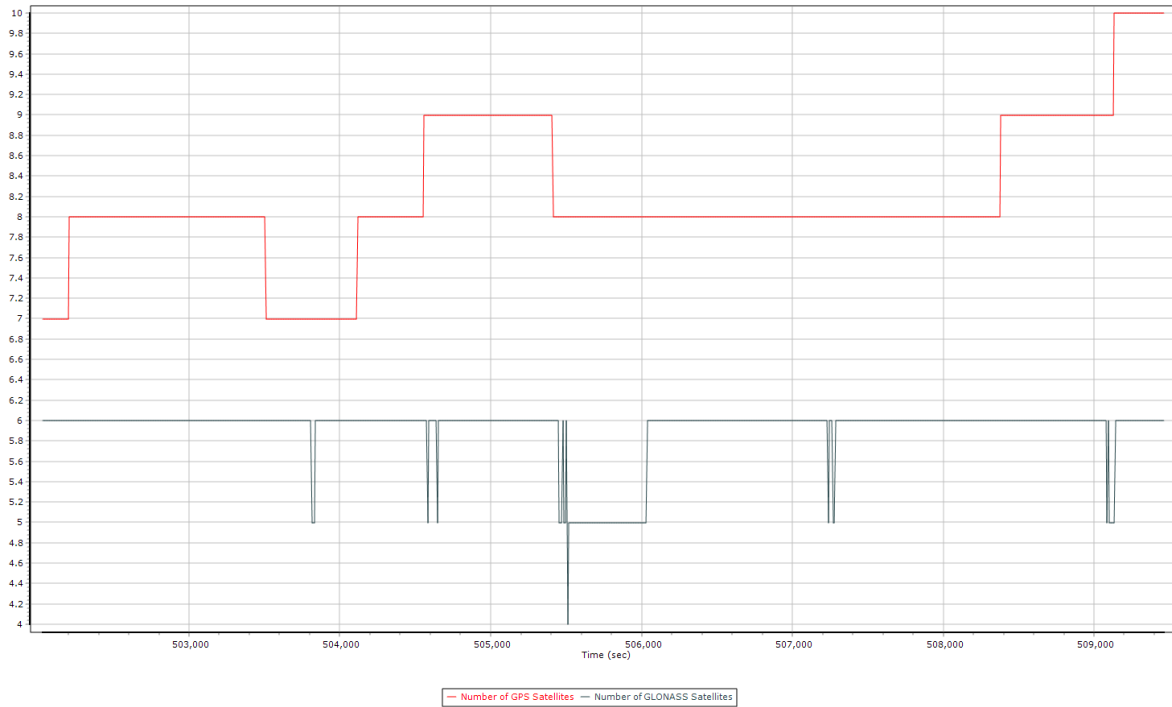
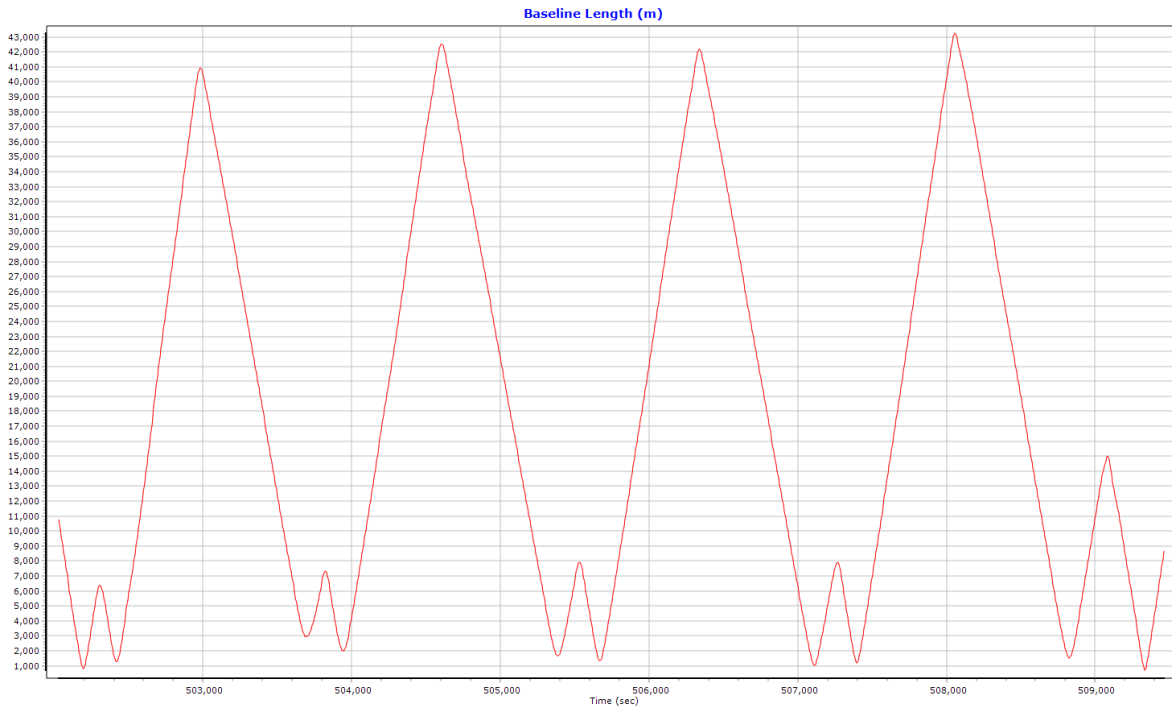
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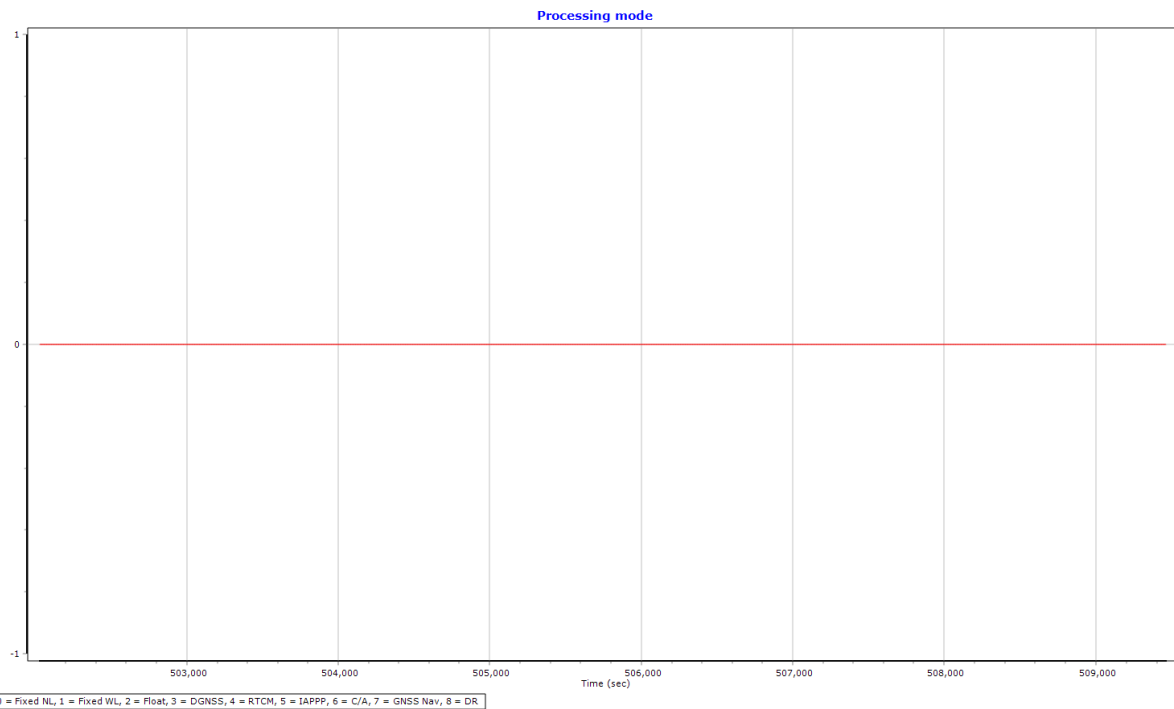
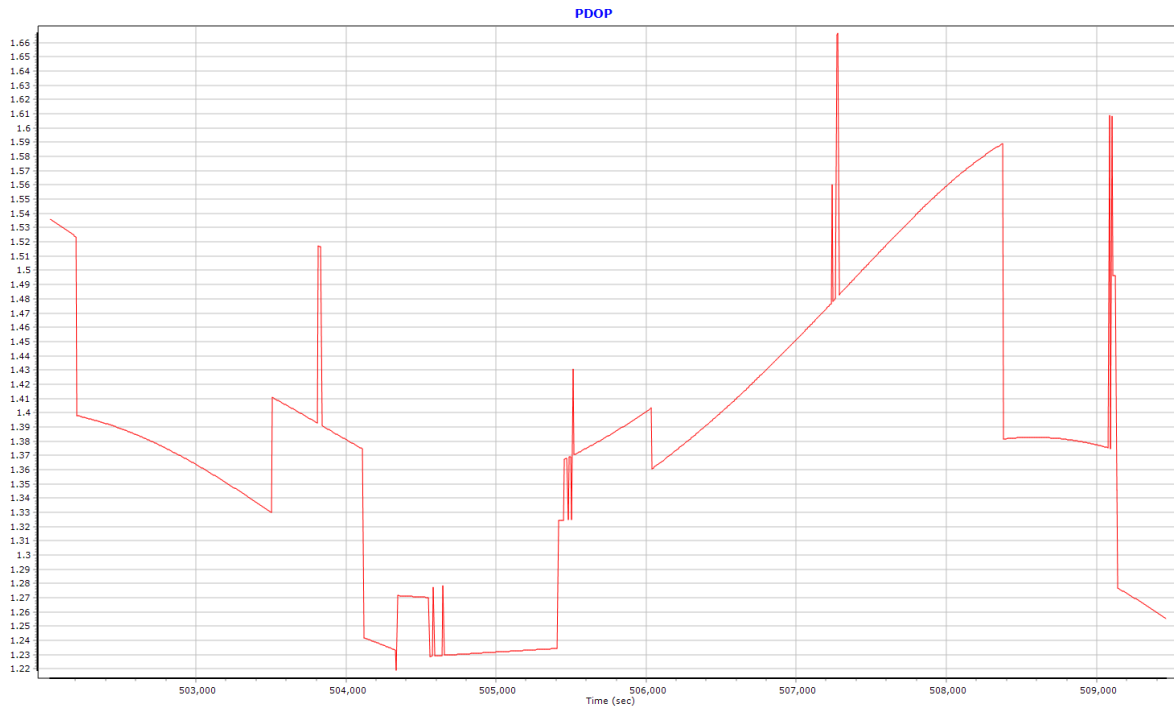




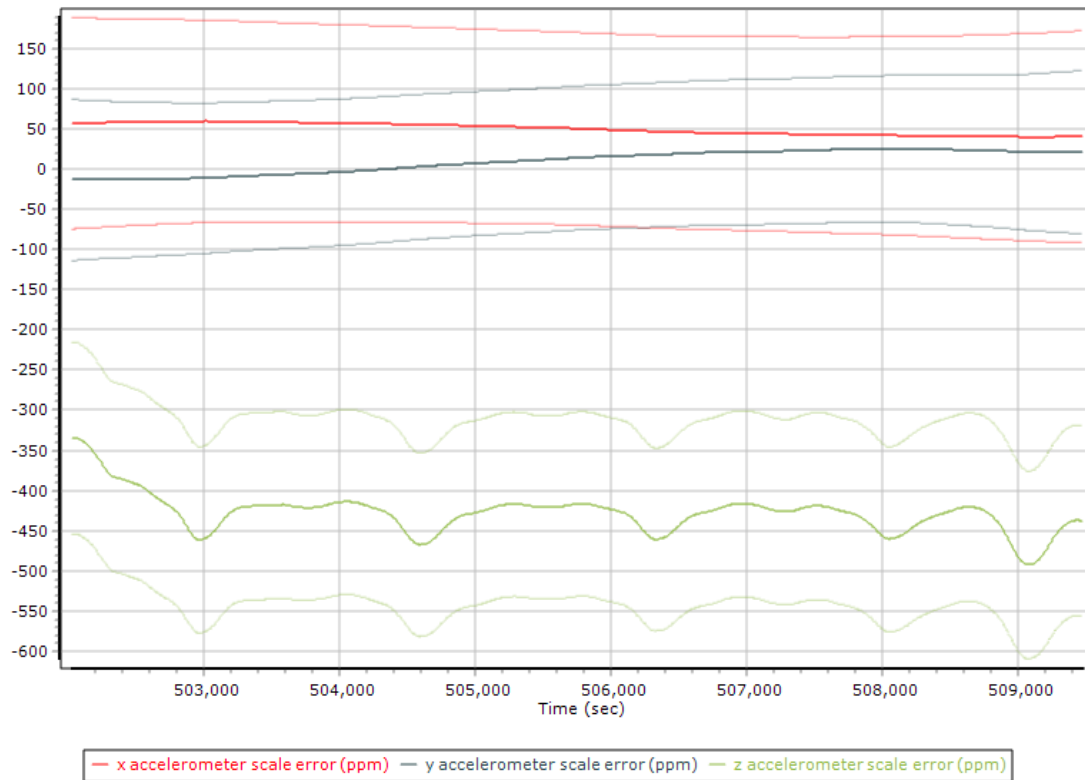
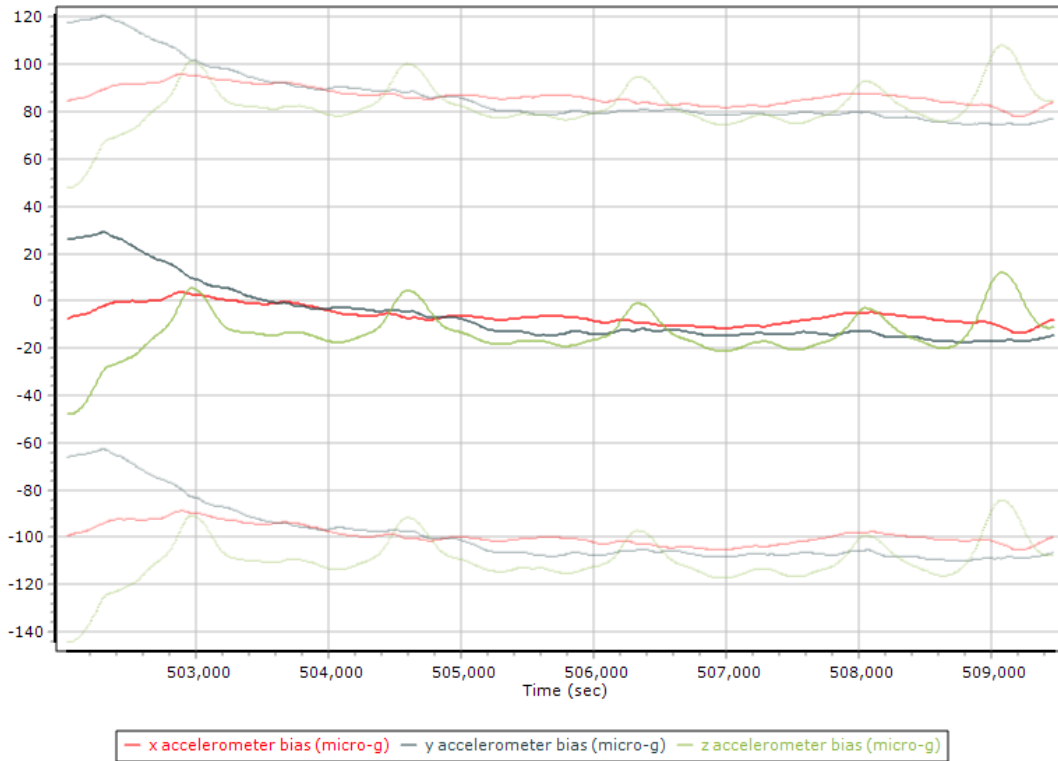


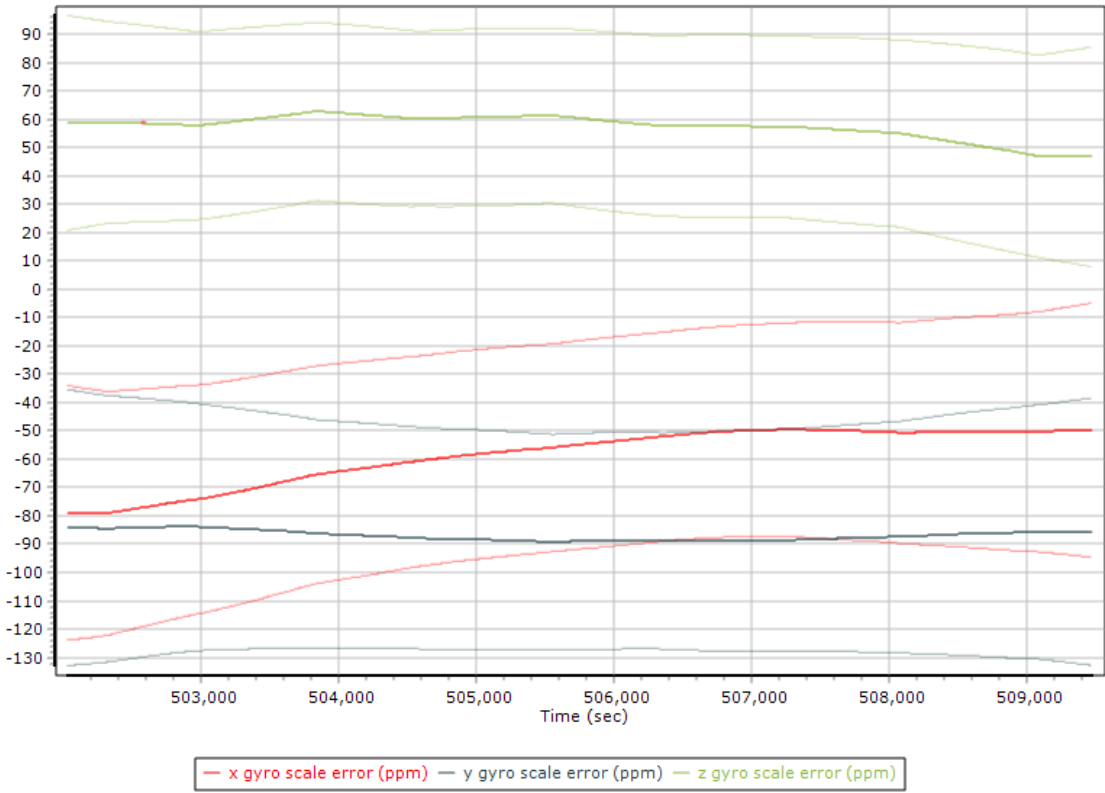
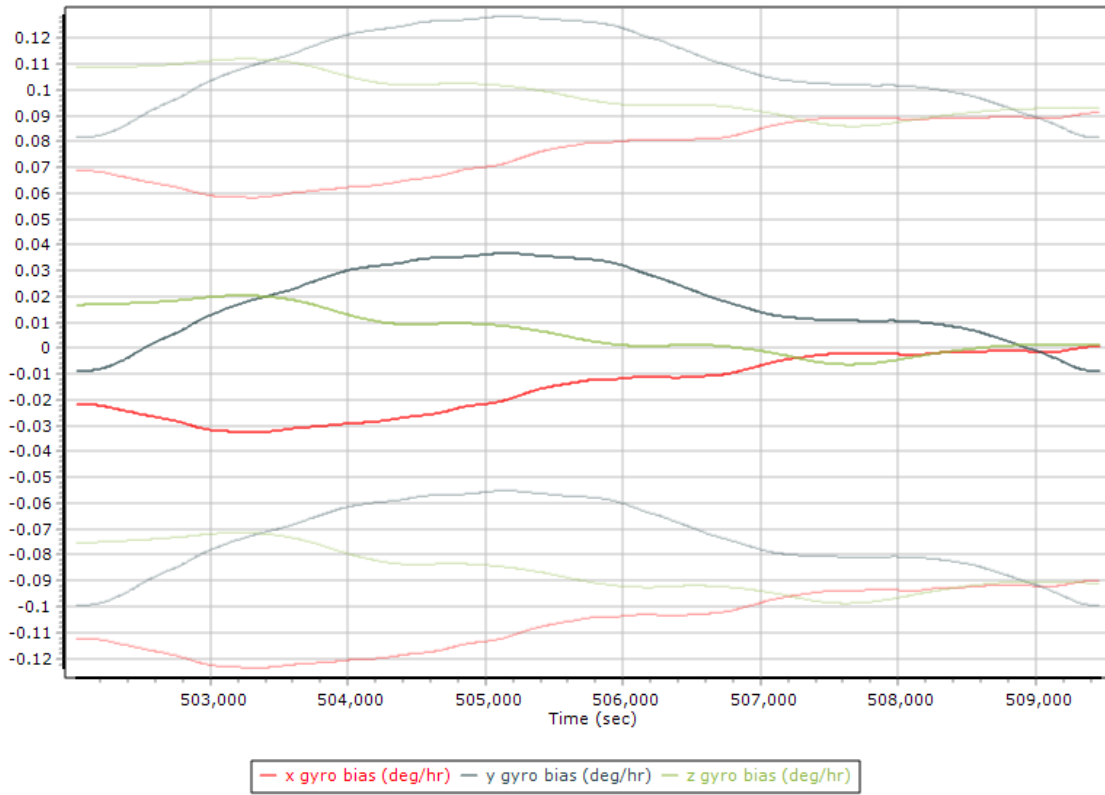




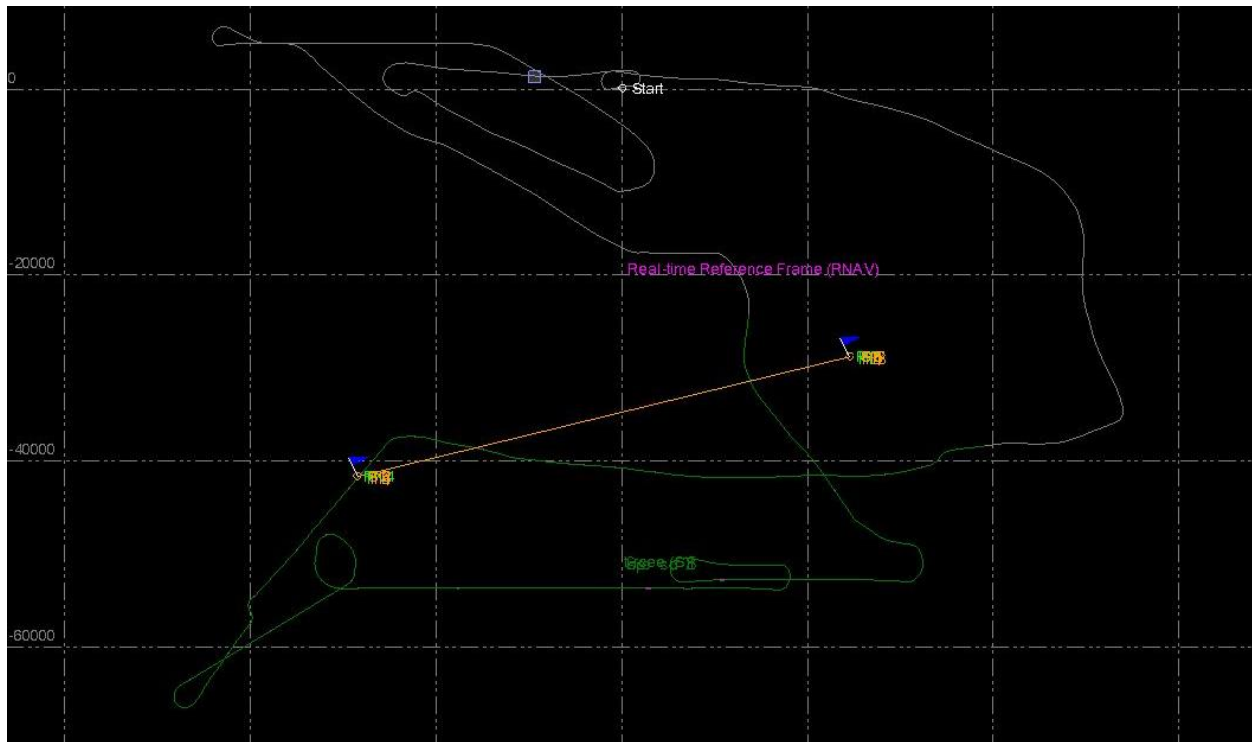


Sensor Errors





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Project Settings

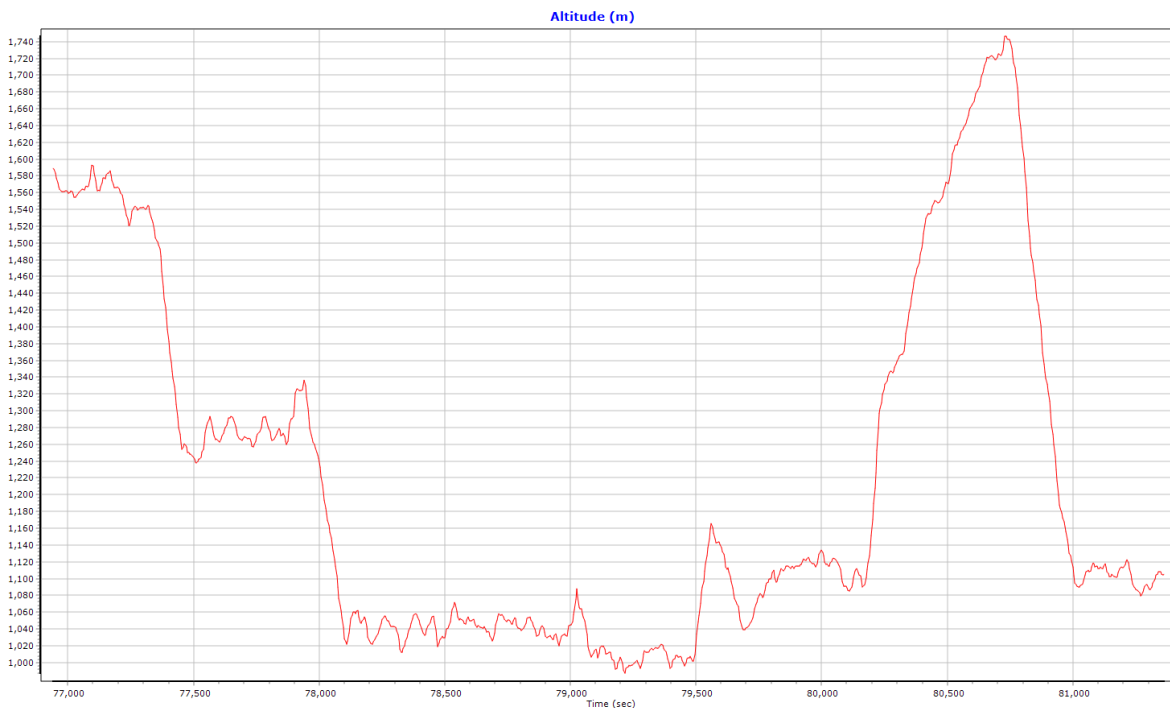
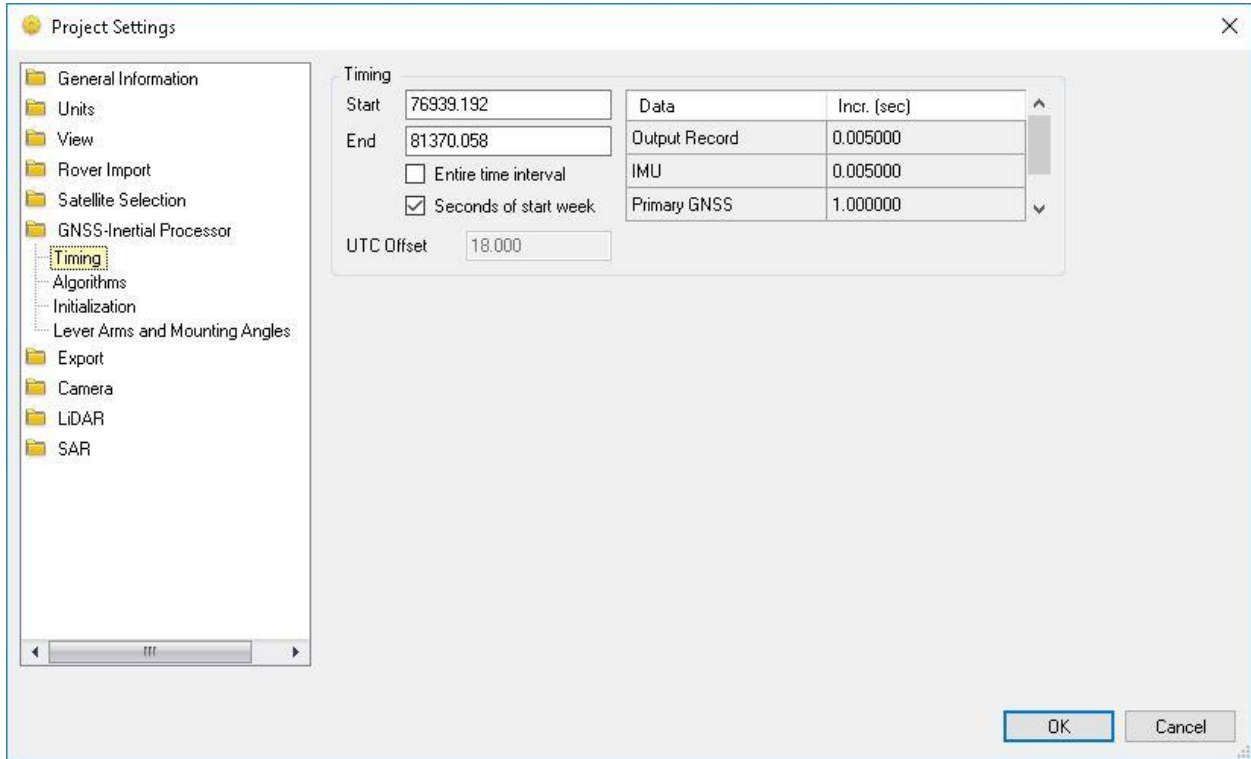
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LIDAR
- SAR

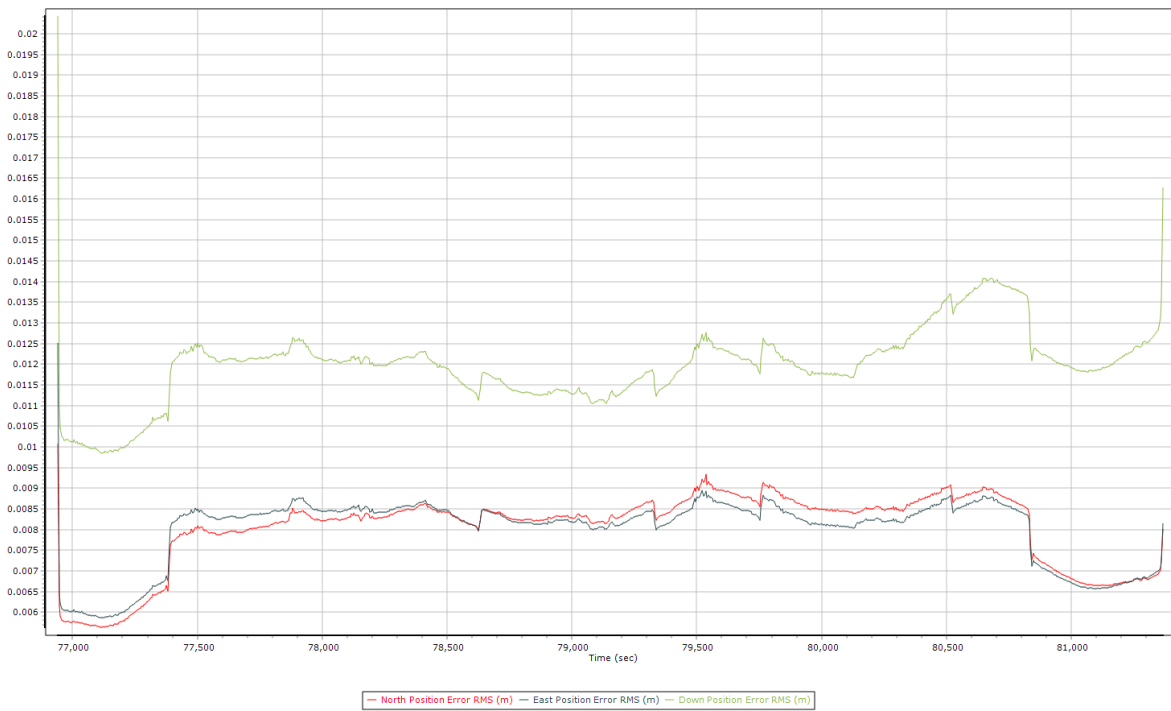
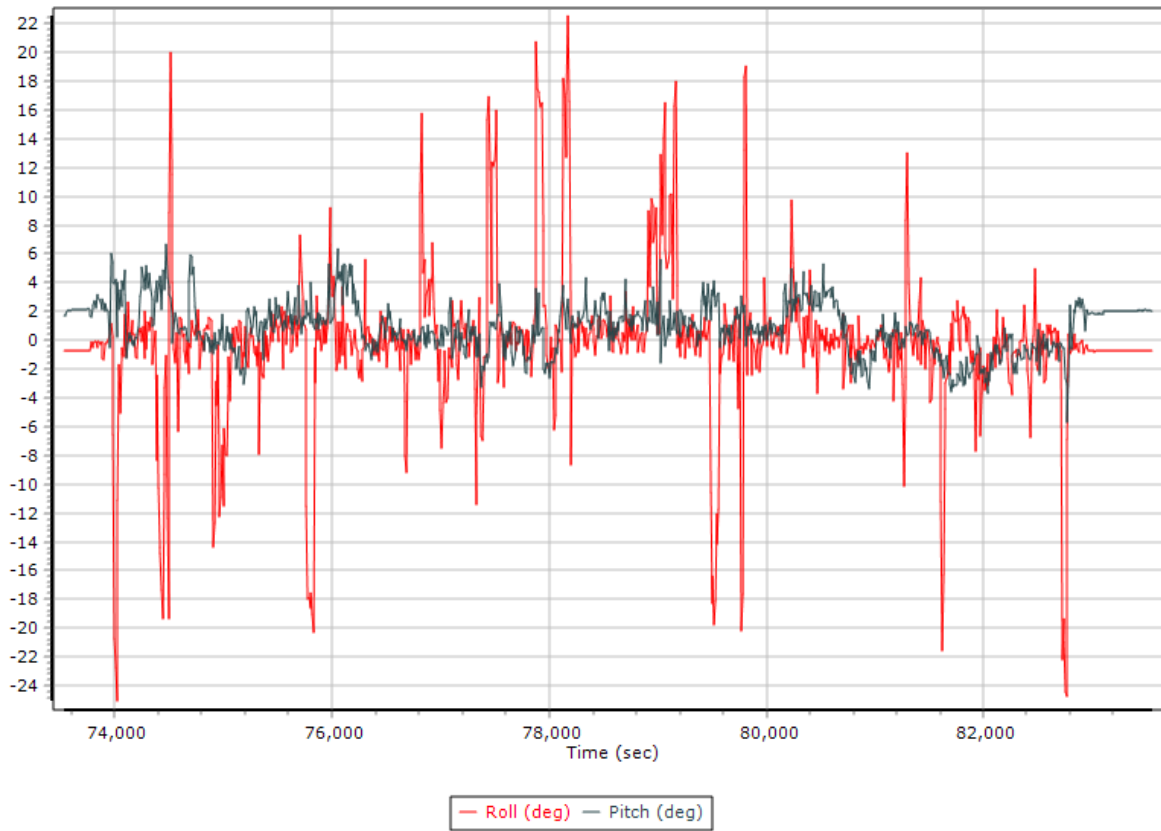
Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.049 m	0.003 m	-1.230 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

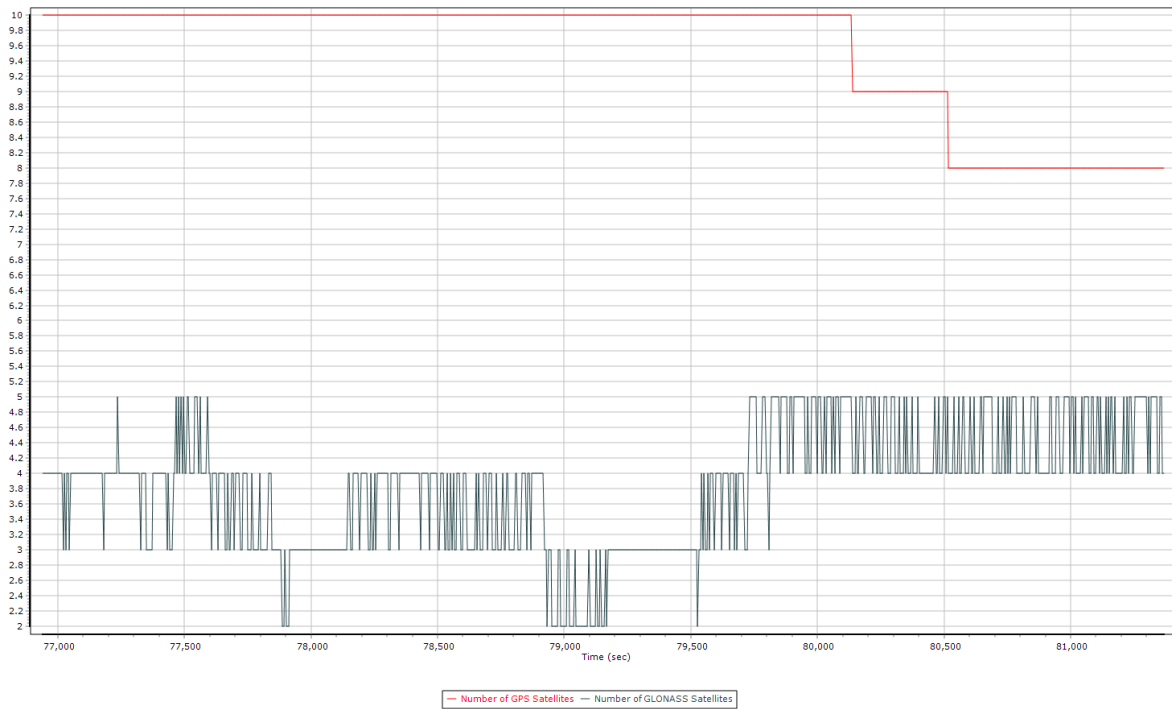
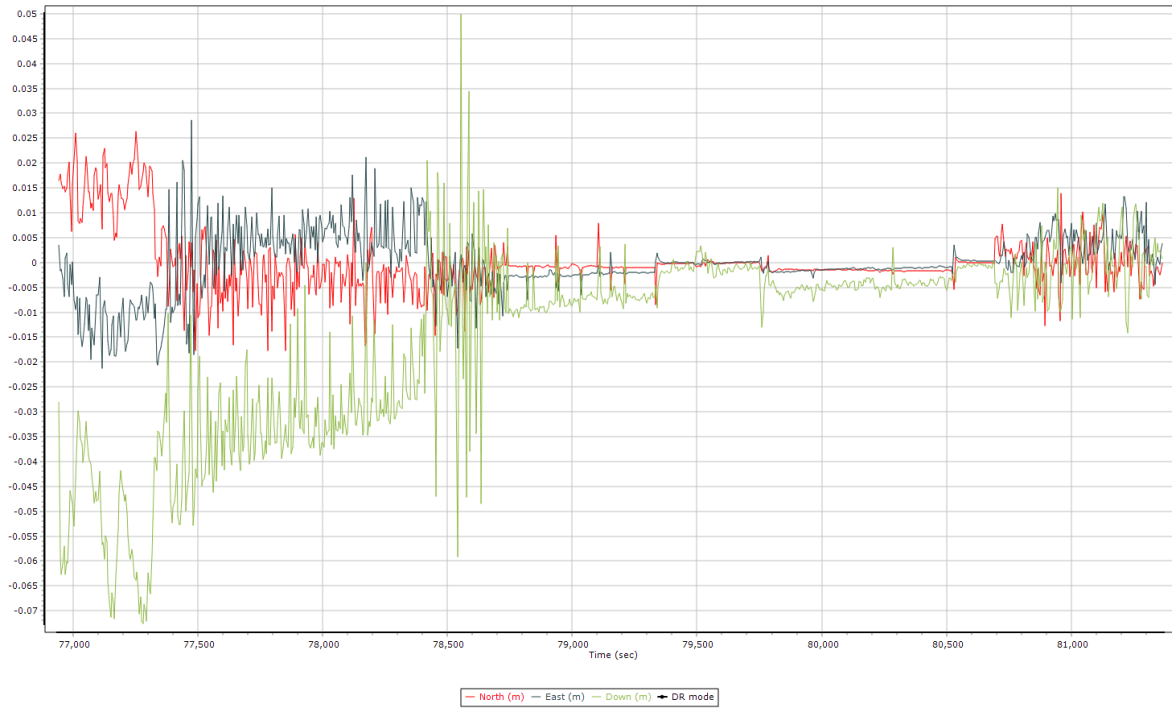
Standard Deviation: <3cm 10cm 50cm 1m 10m

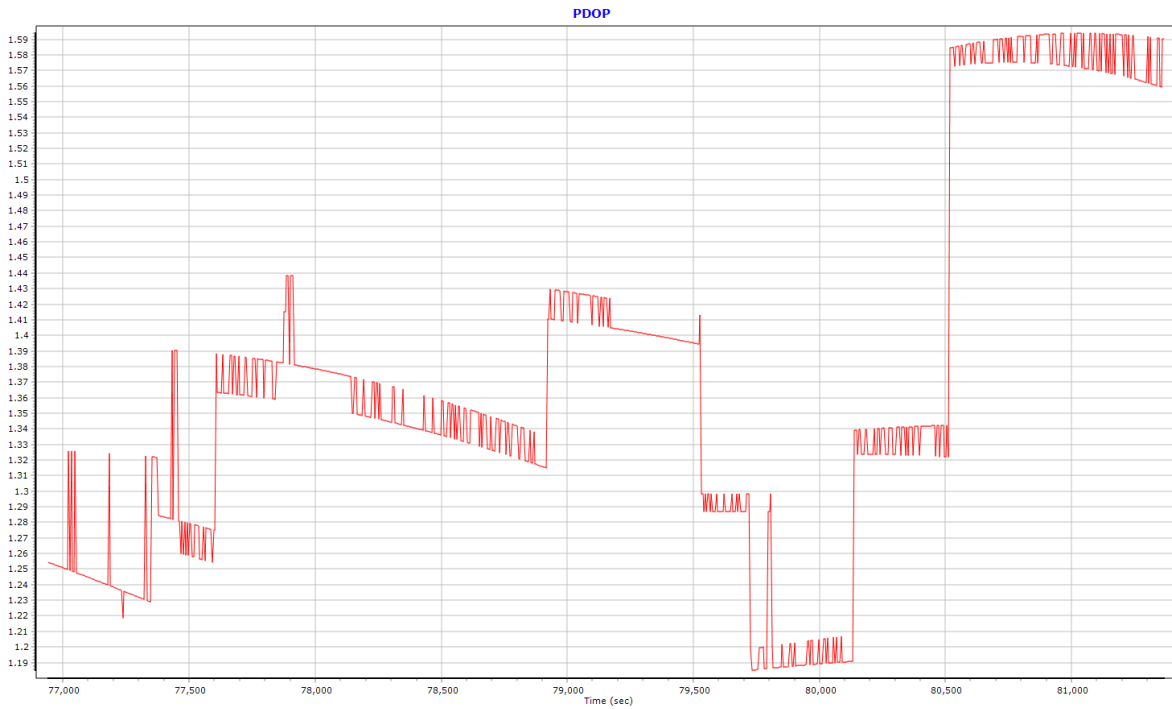
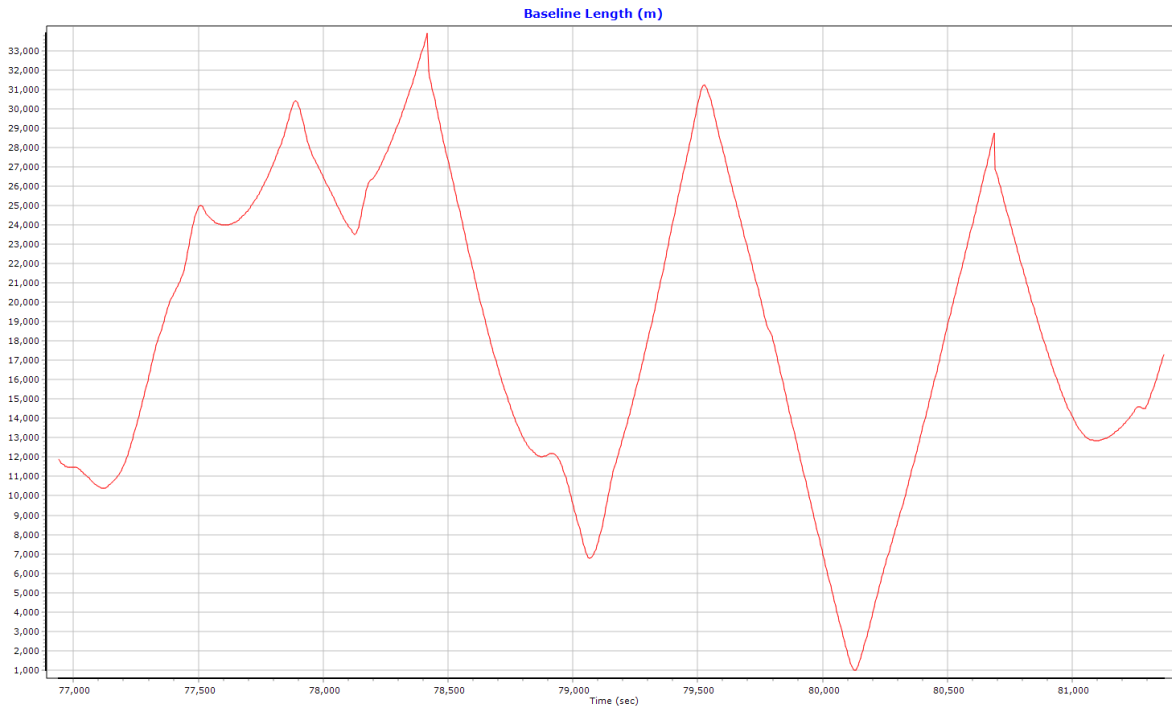
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

OK Cancel



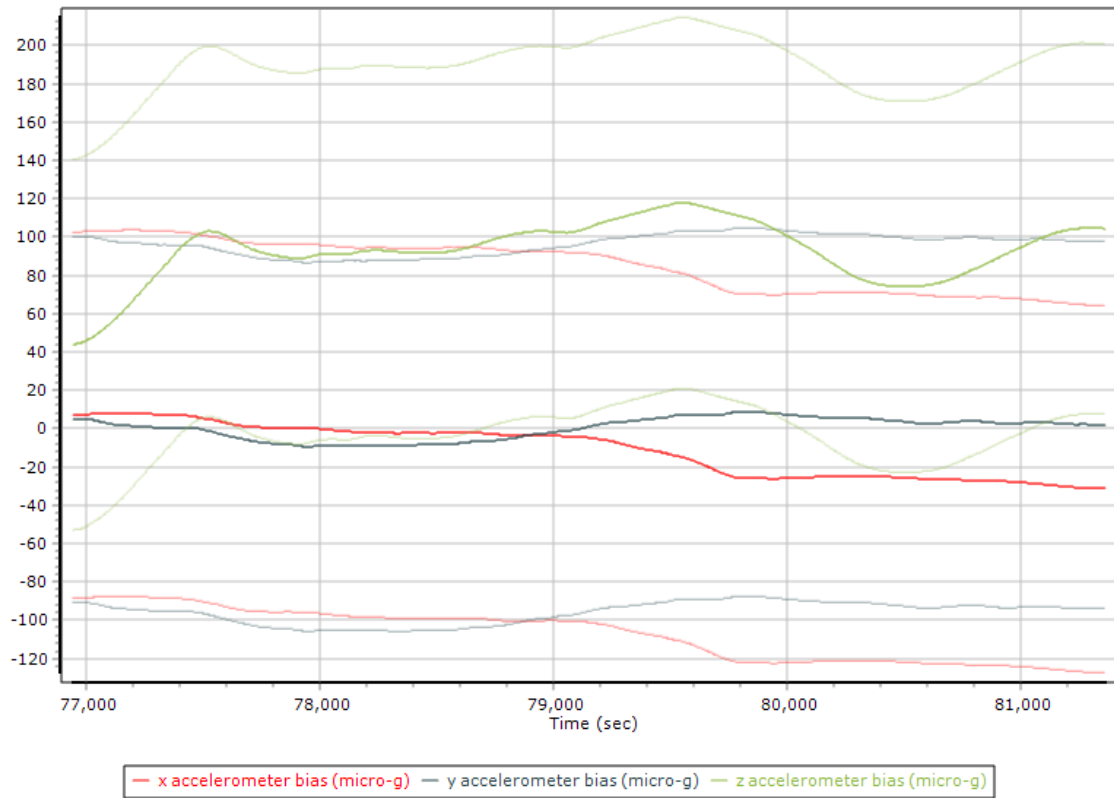


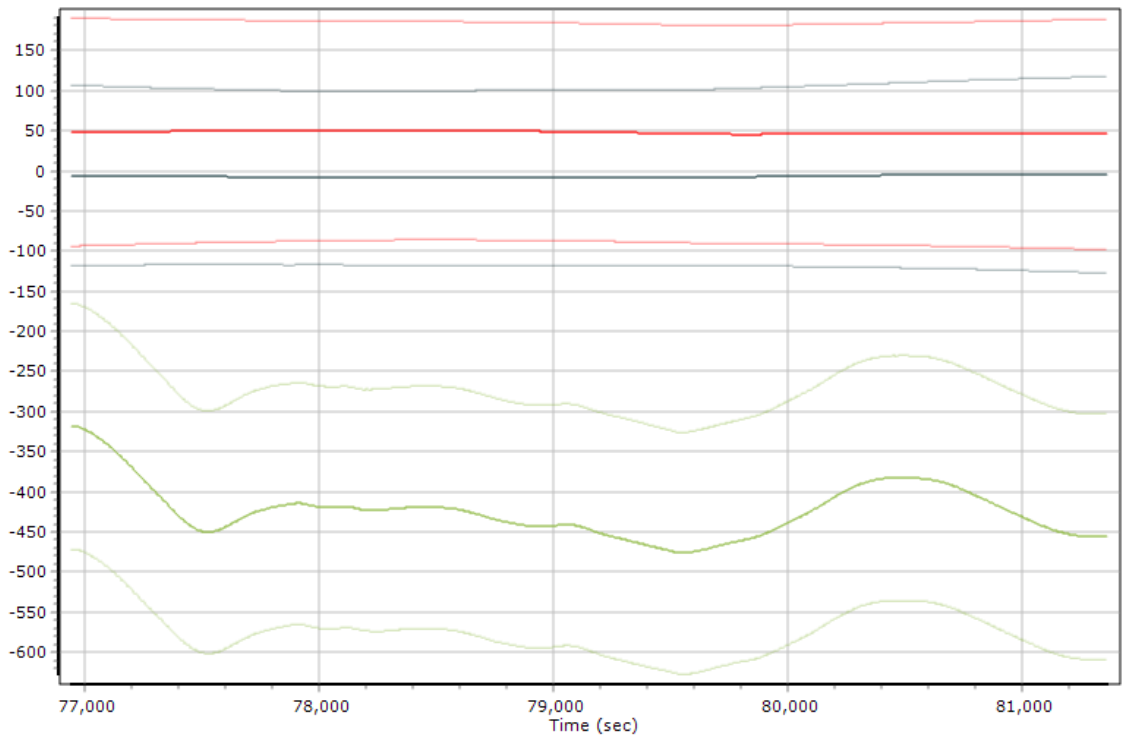




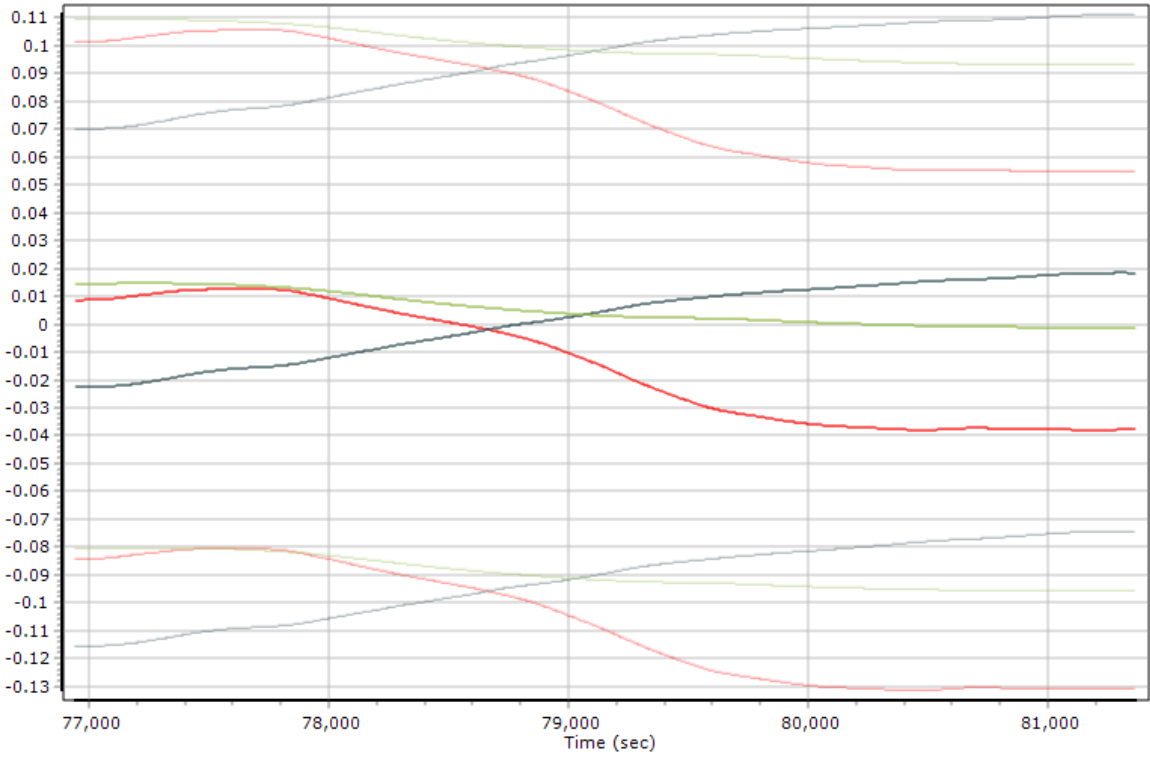


Sensor Errors

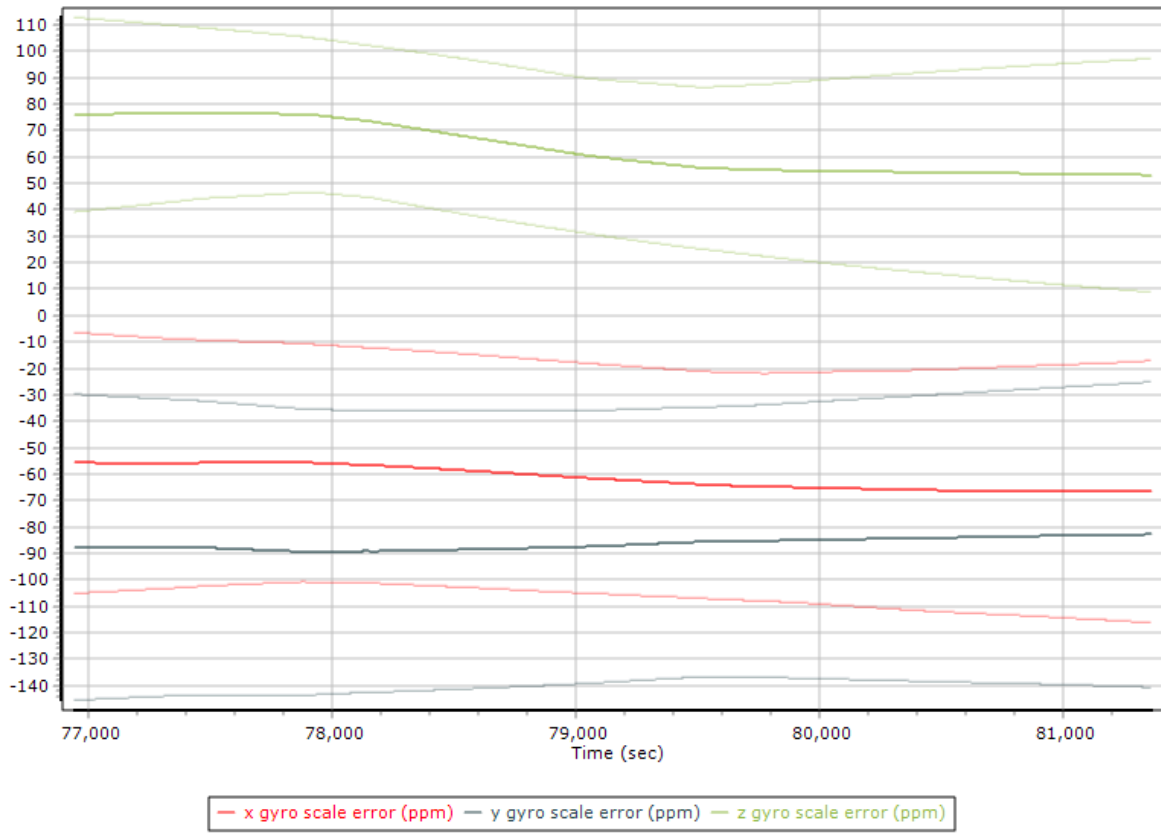




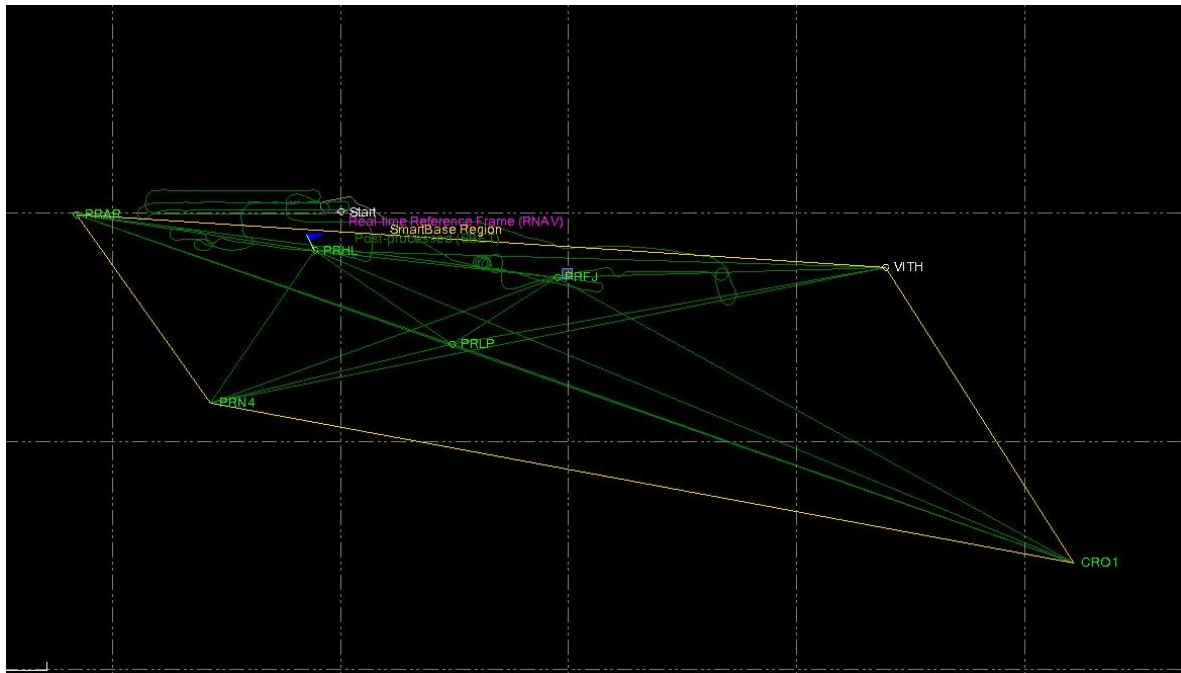
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

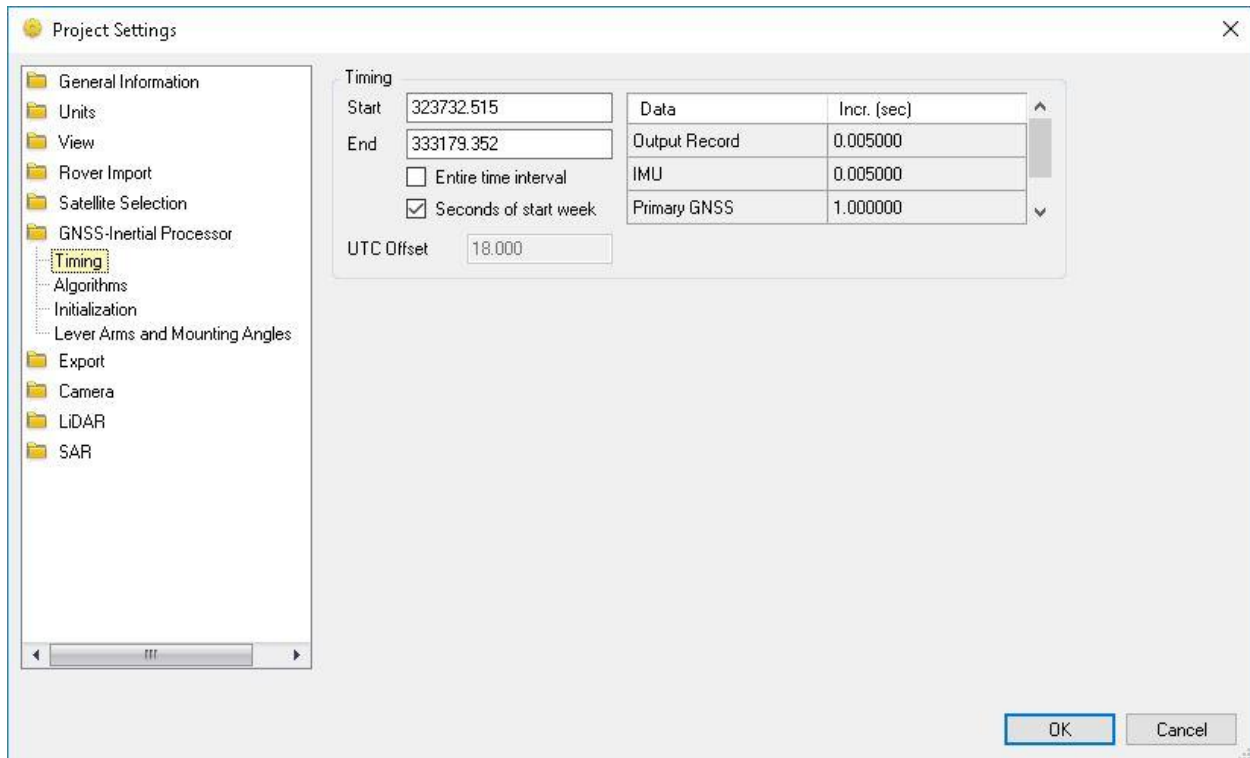
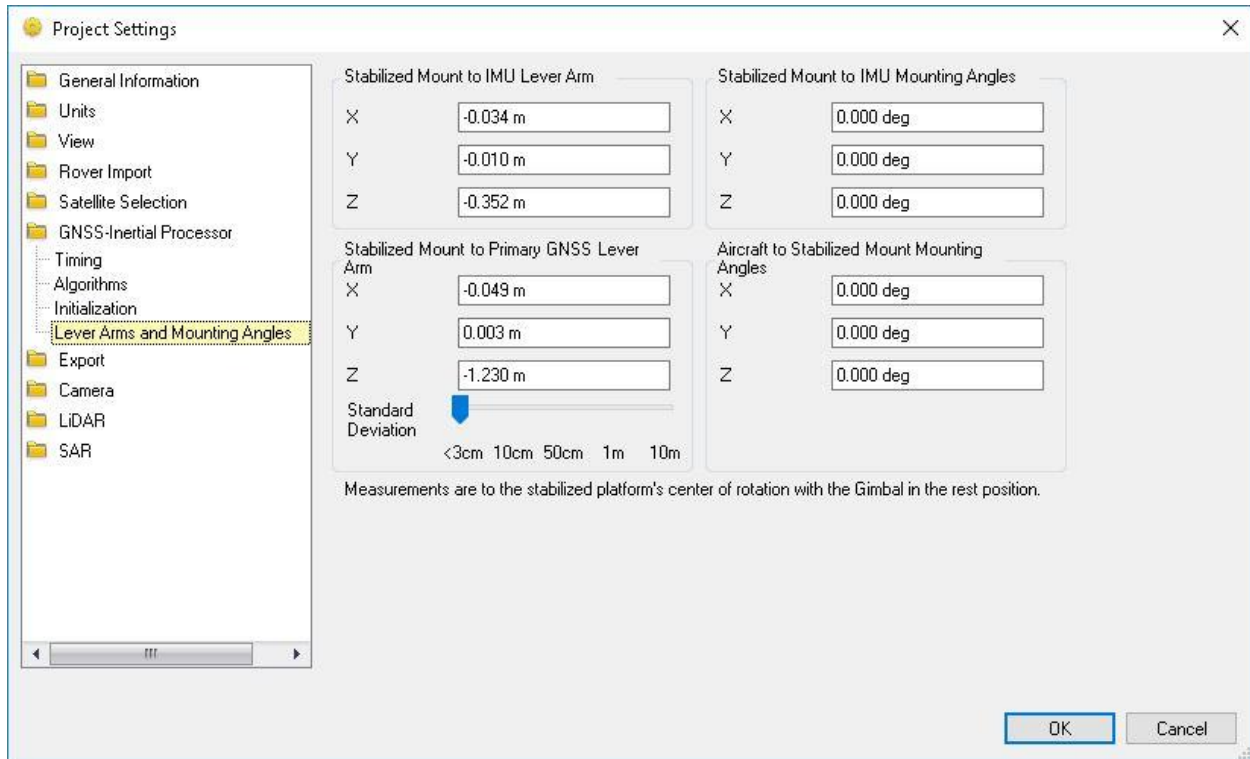


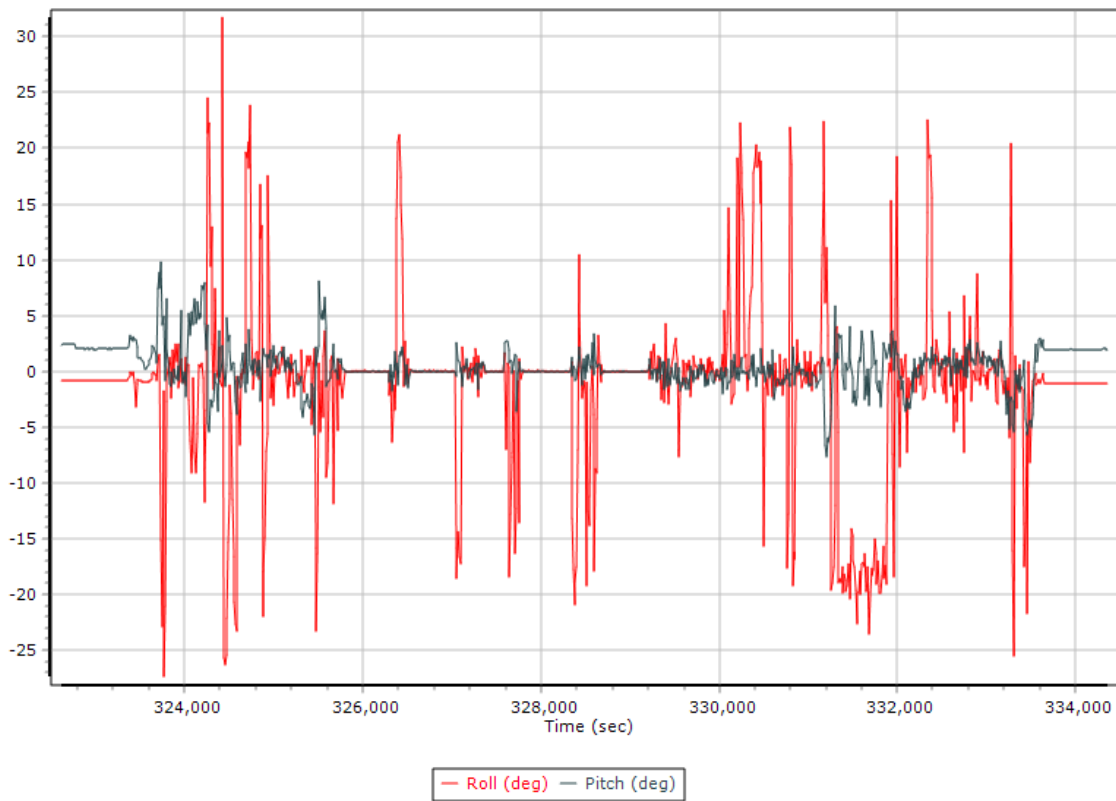
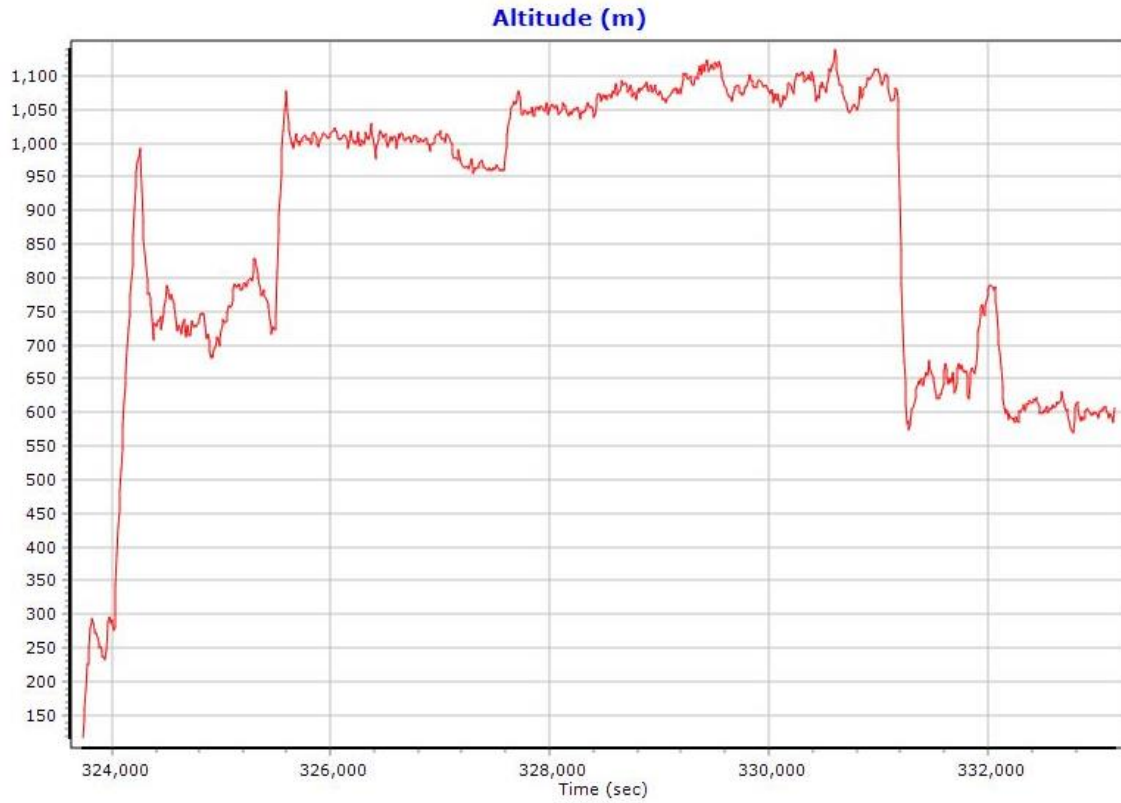
— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

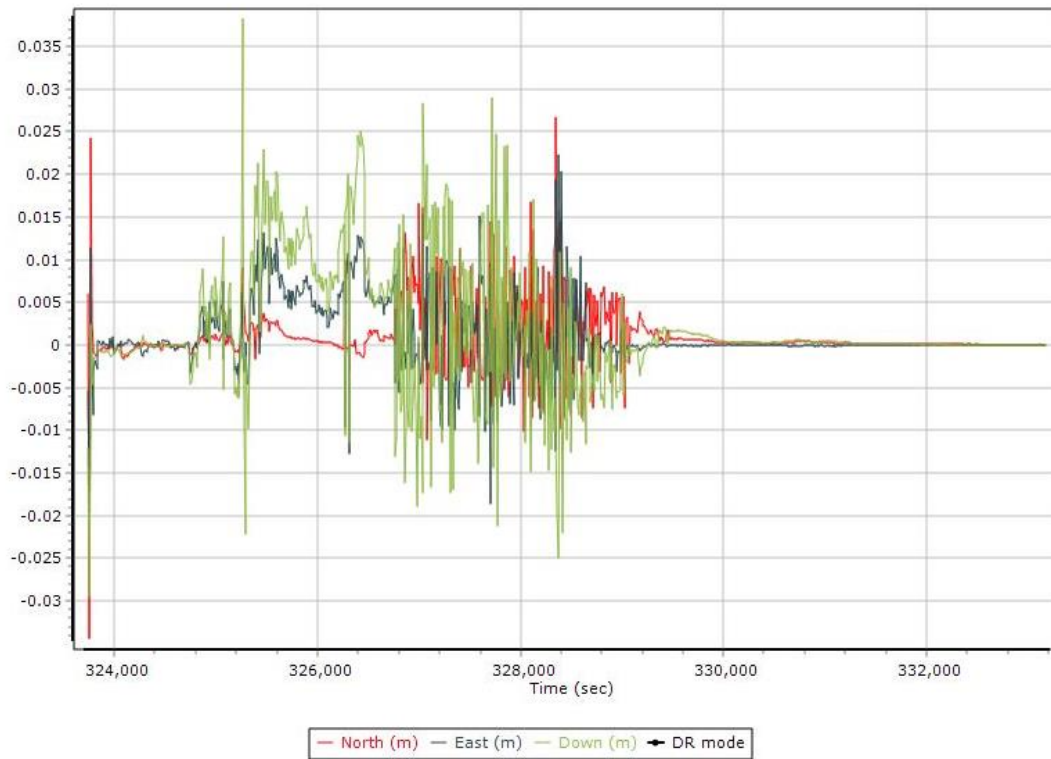
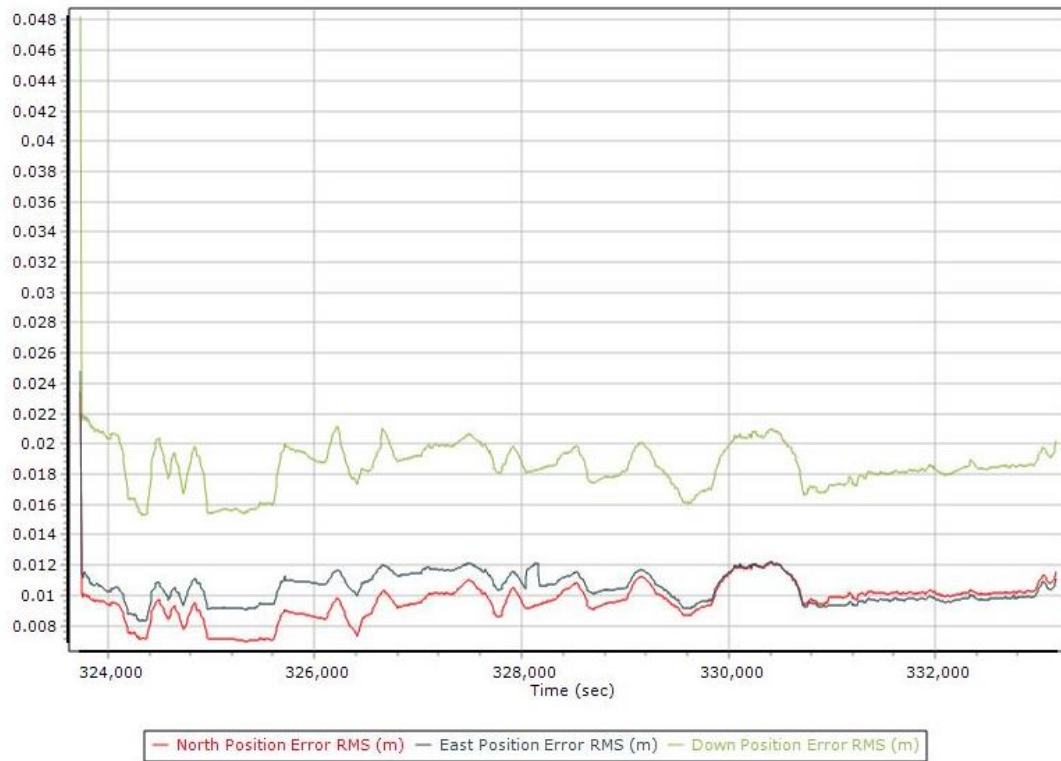


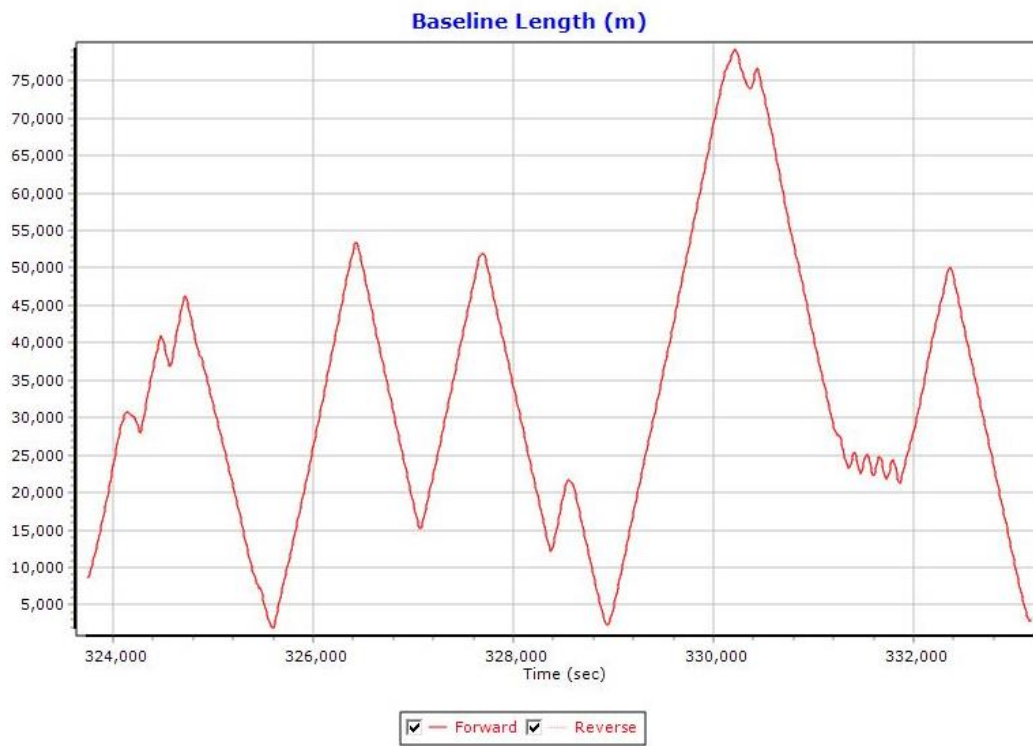
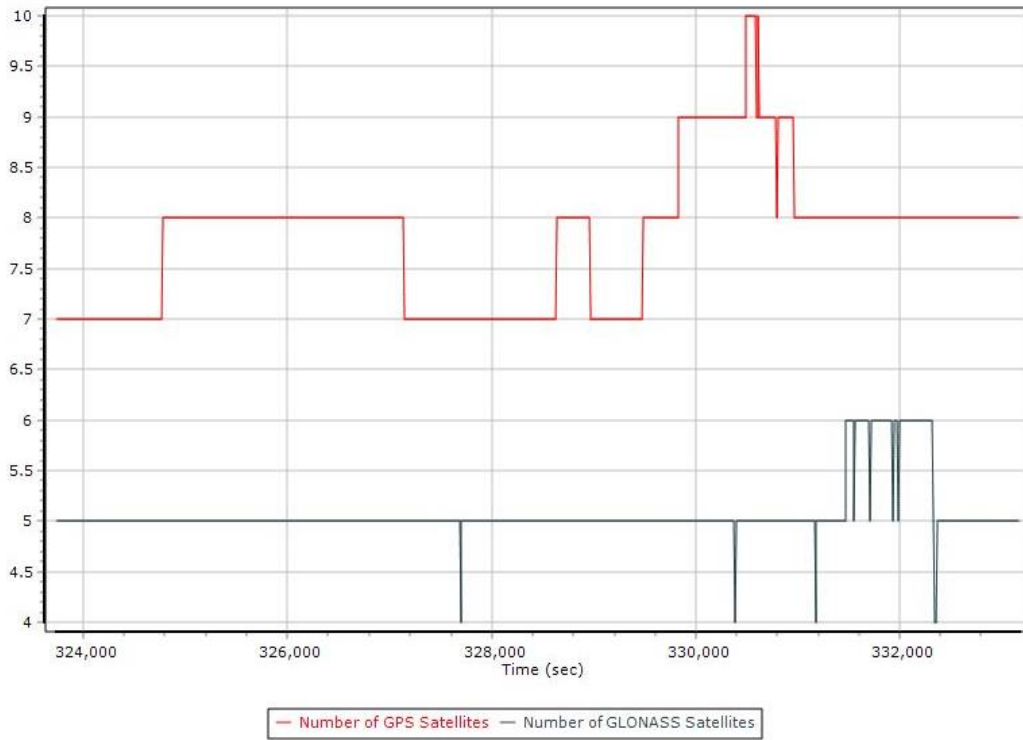
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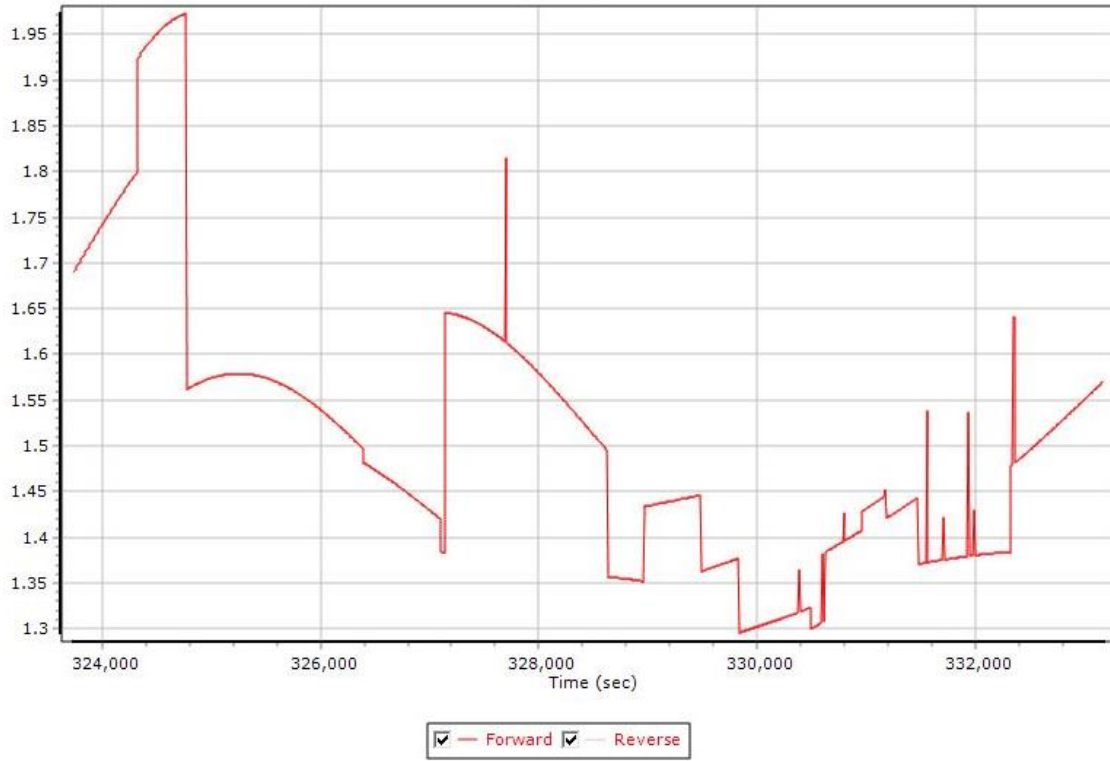




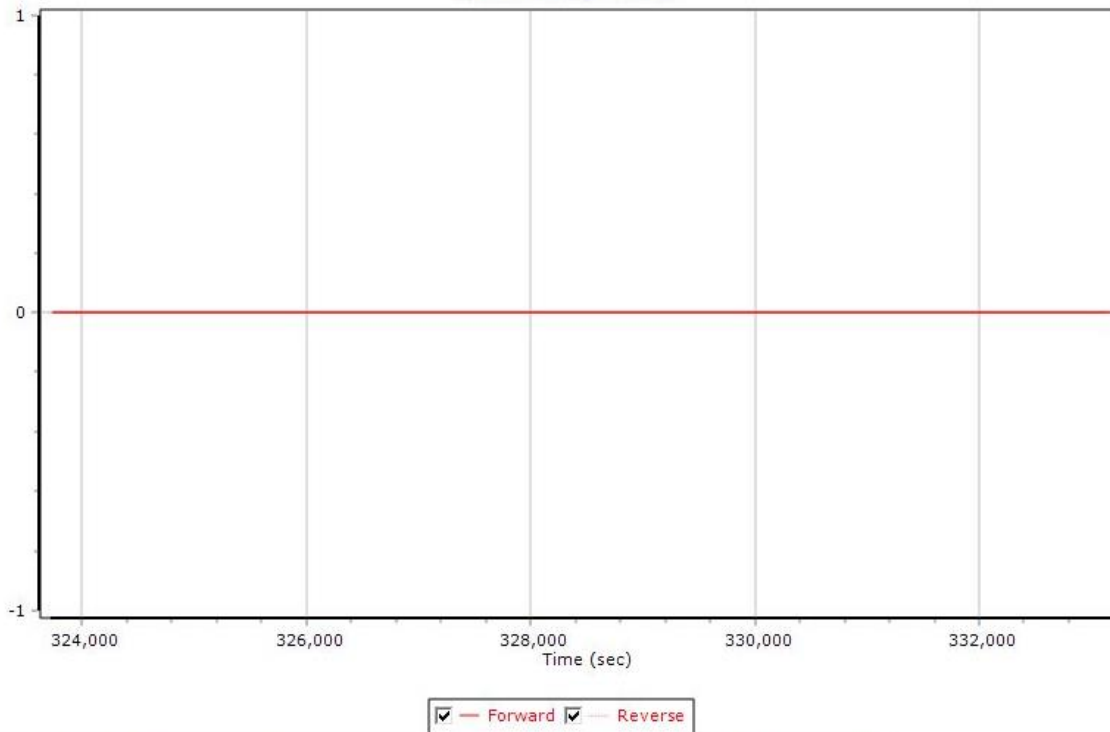




PDOP

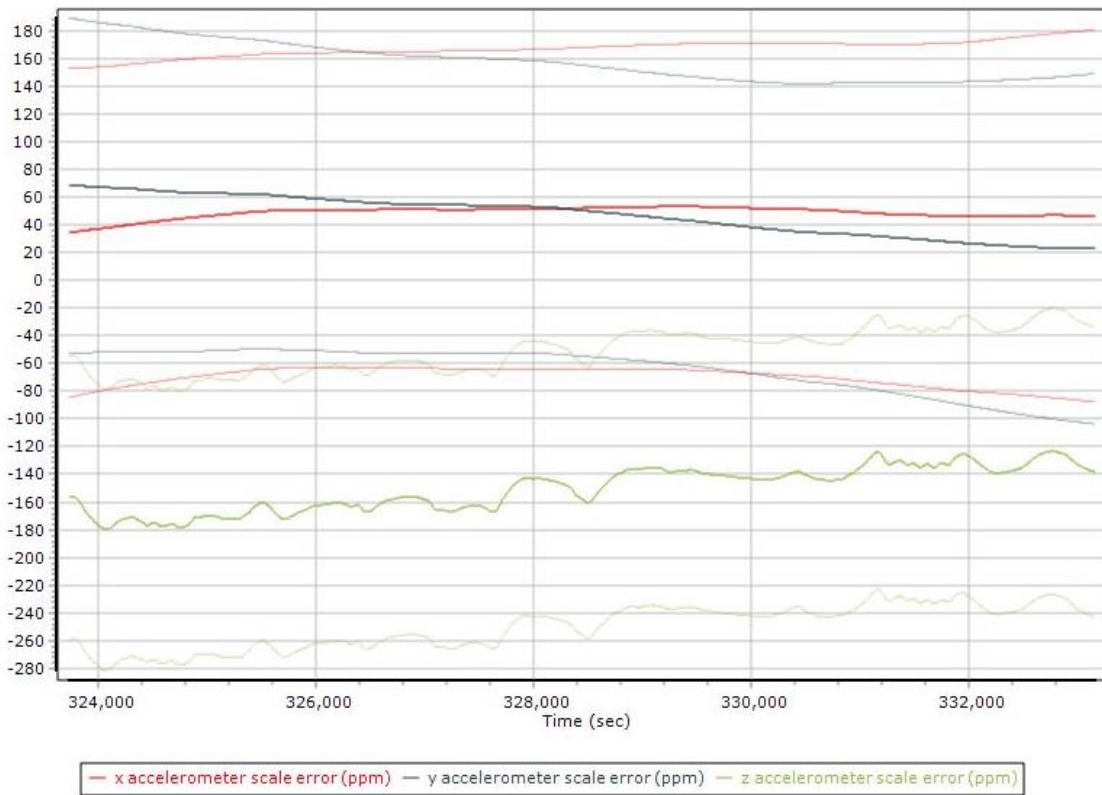
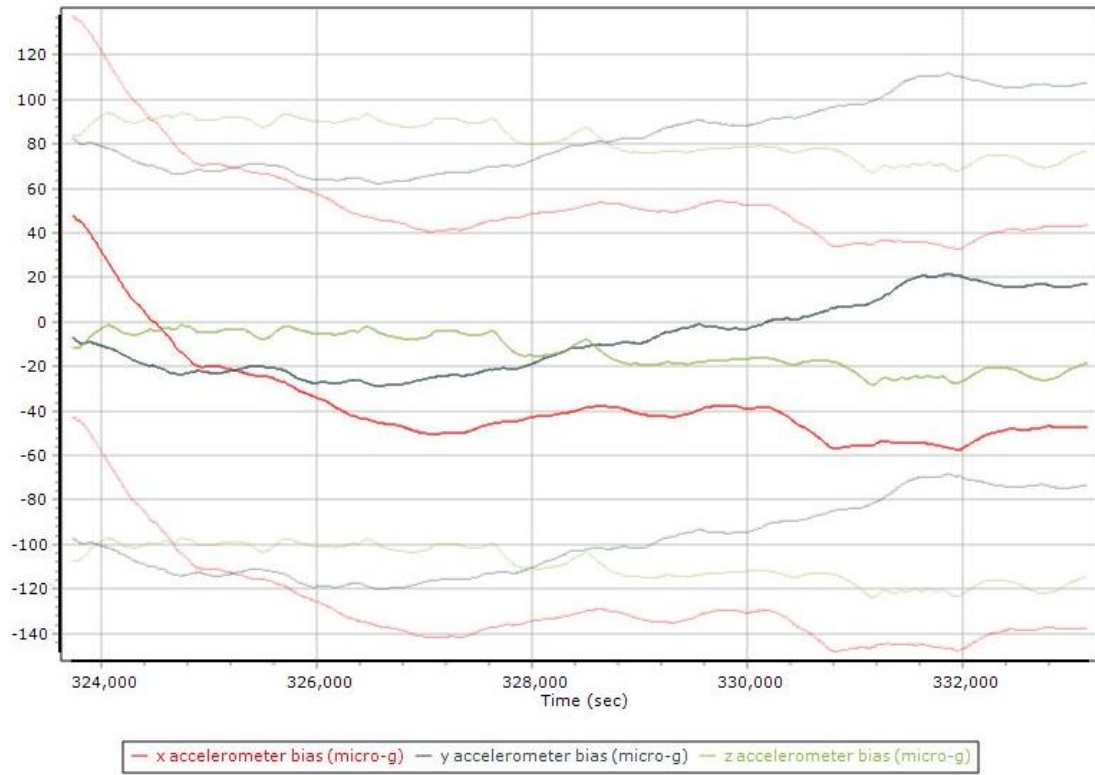


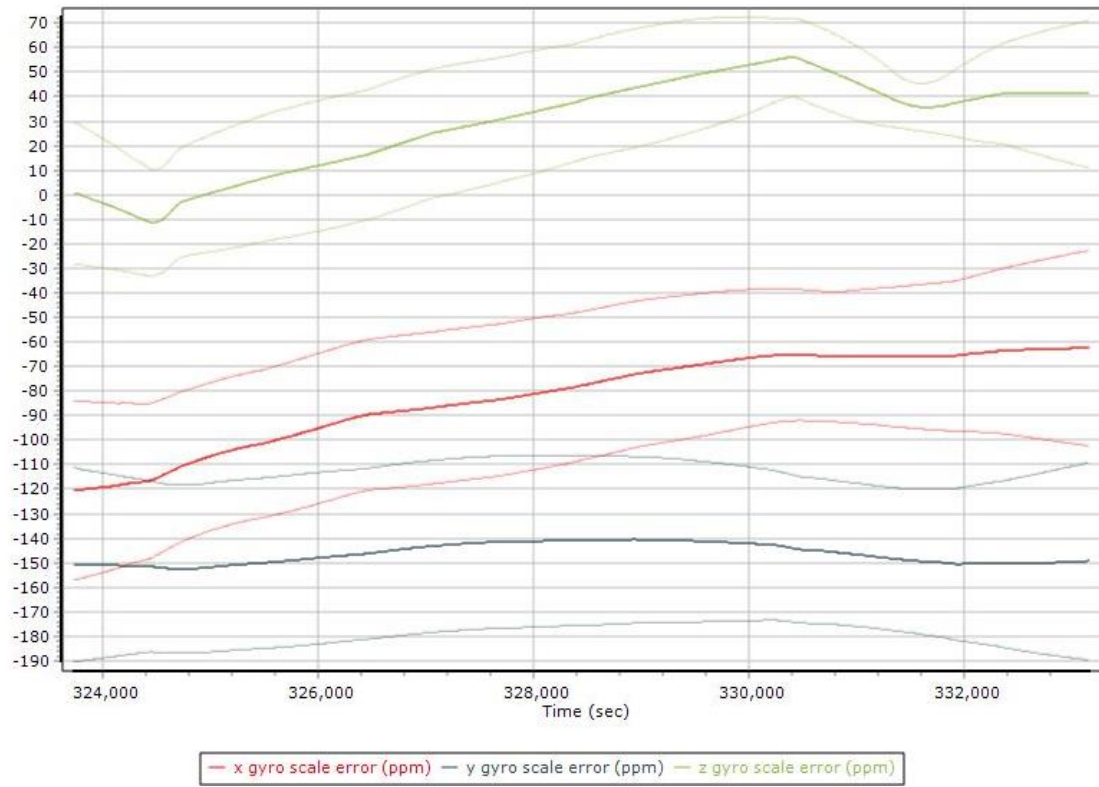
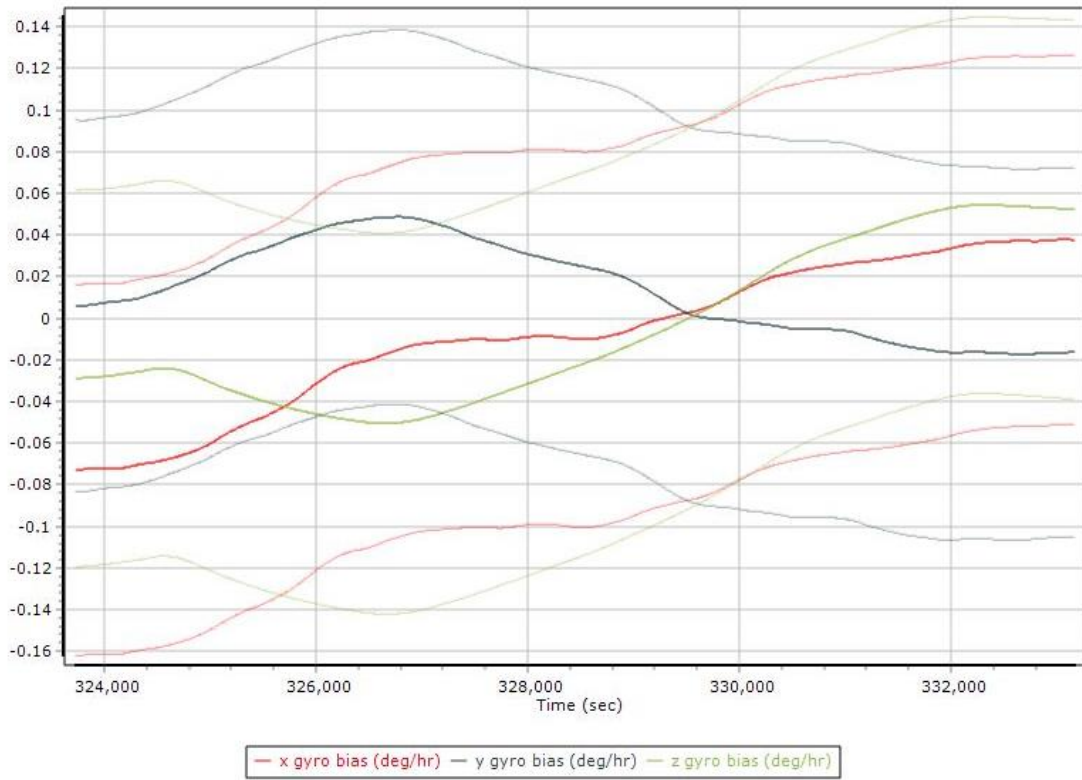
Processing mode



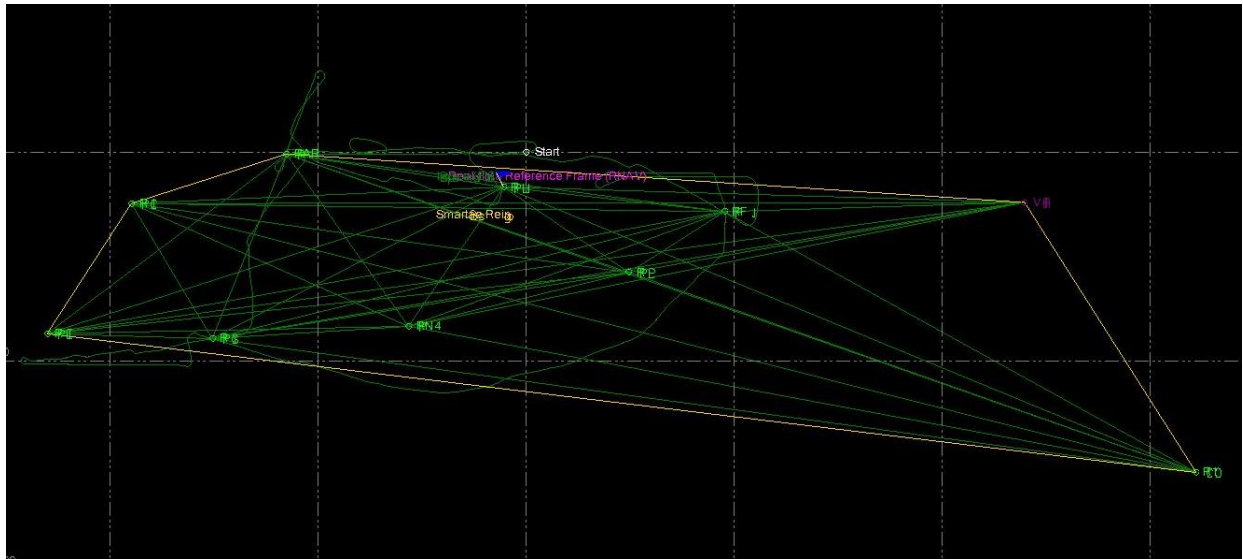
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





45A18299A



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

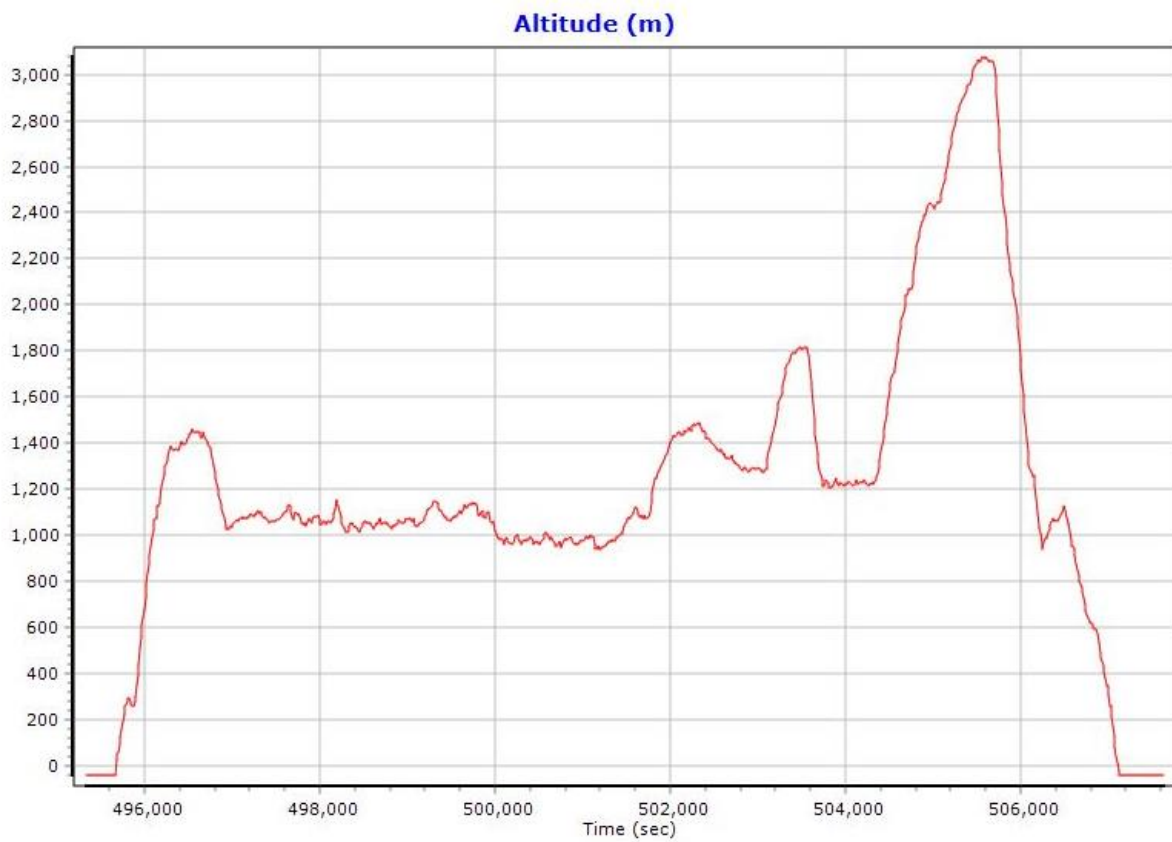
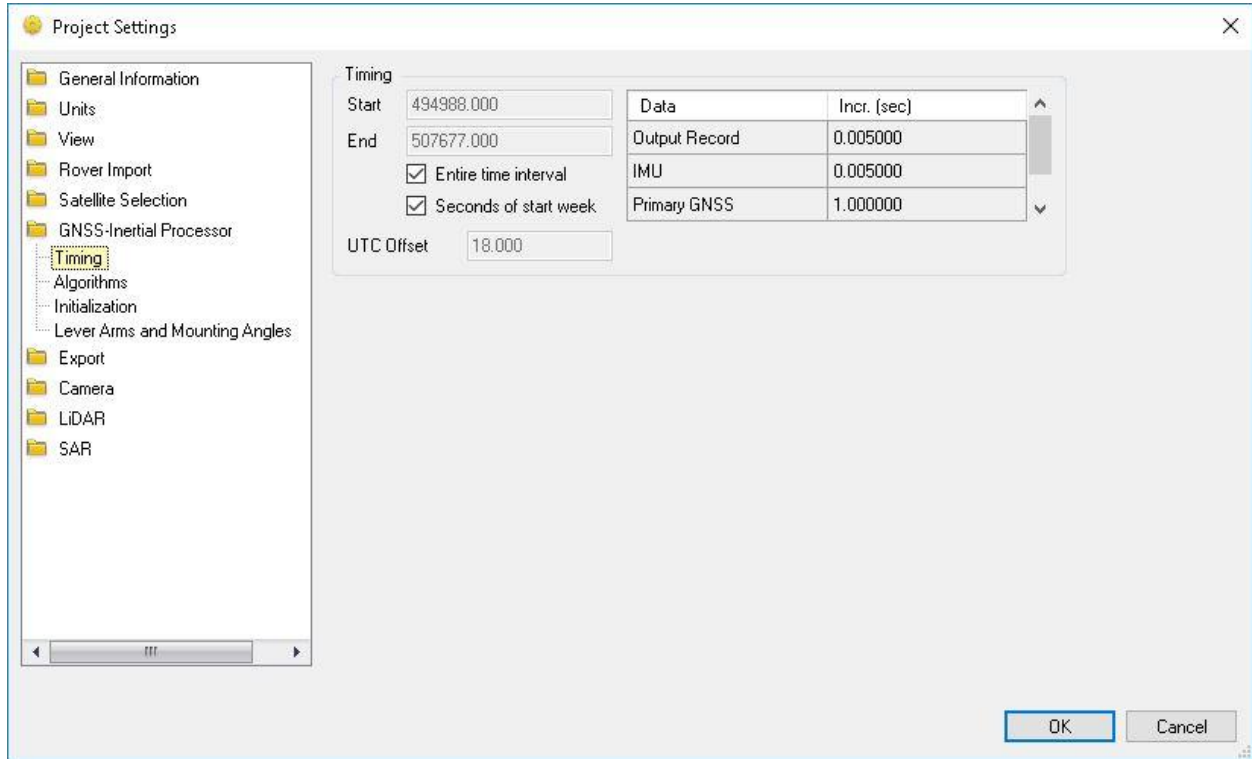
Stabilized Mount to IMU Lever Arm	Stabilized Mount to IMU Mounting Angles
X: -0.034 m	X: 0.000 deg
Y: -0.010 m	Y: 0.000 deg
Z: -0.352 m	Z: 0.000 deg

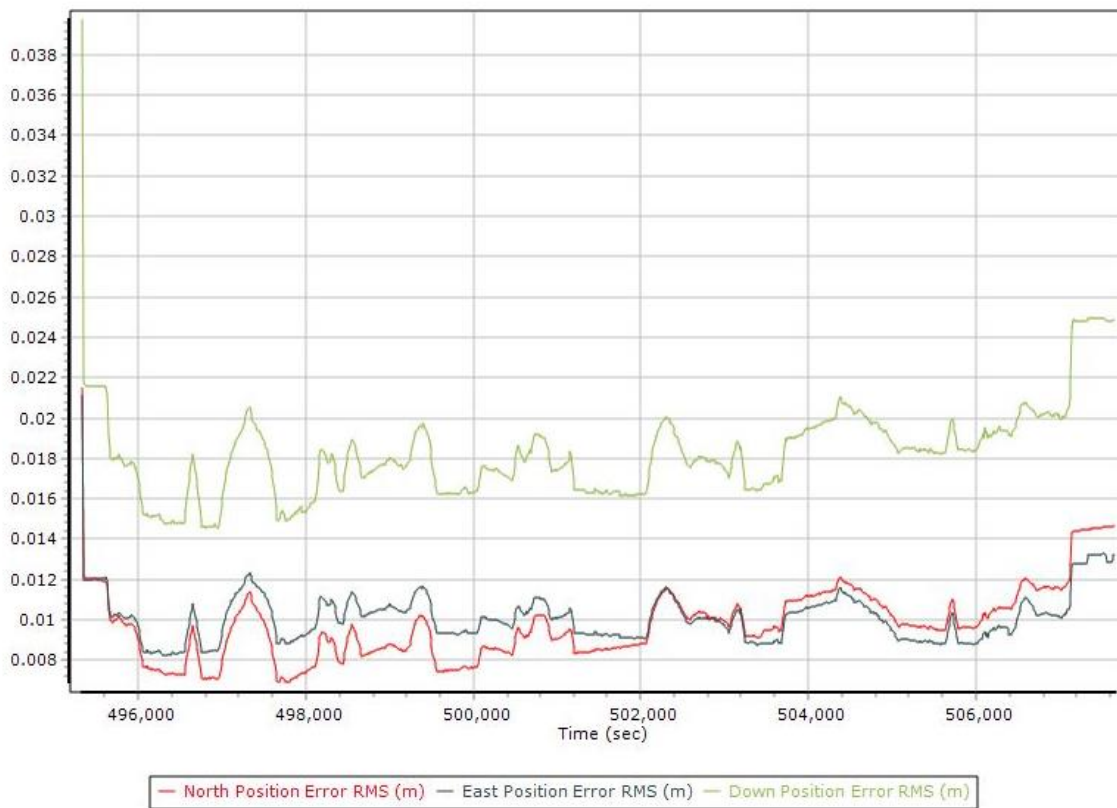
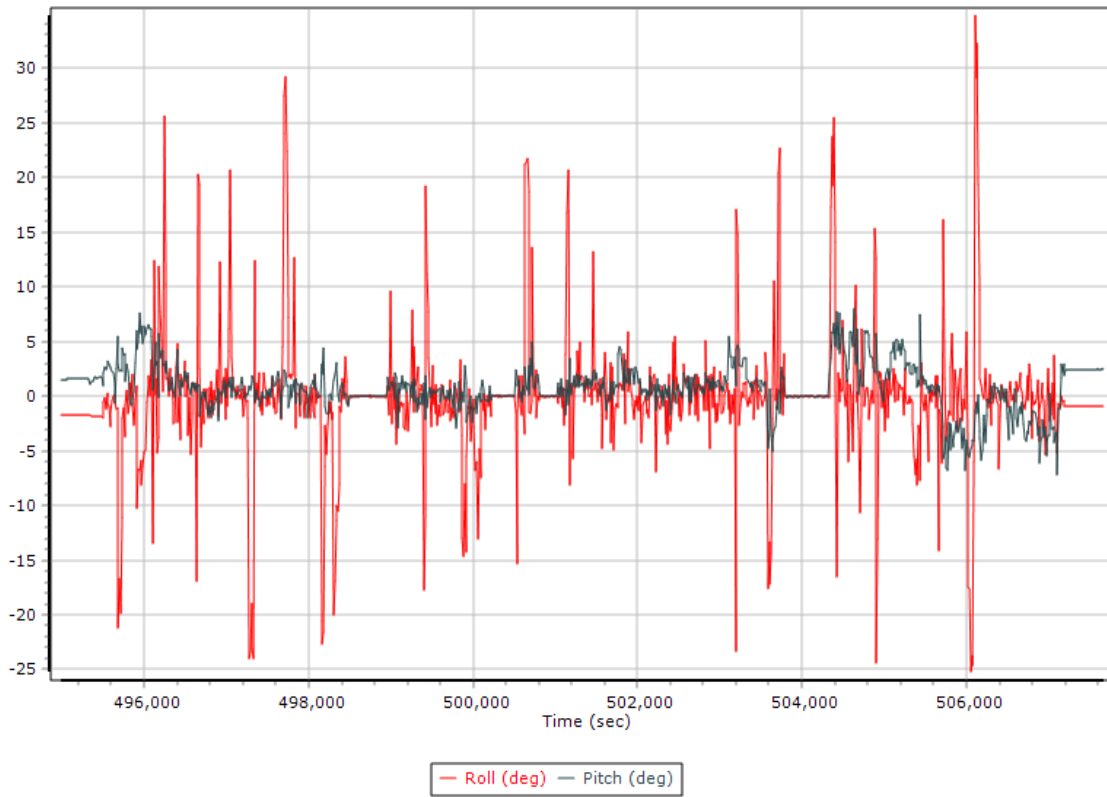
Stabilized Mount to Primary GNSS Lever Arm	Aircraft to Stabilized Mount Mounting Angles
X: -0.049 m	X: 0.000 deg
Y: 0.003 m	Y: 0.000 deg
Z: -1.230 m	Z: 0.000 deg

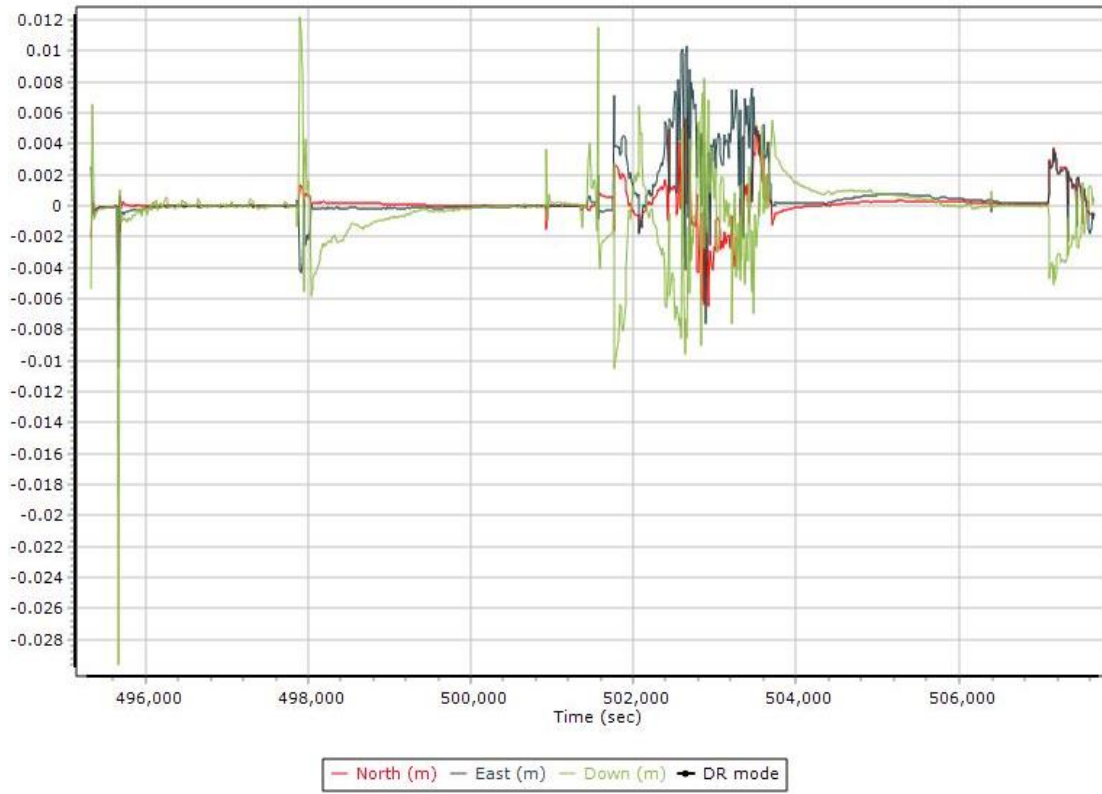
Standard Deviation: <3cm 10cm 50cm 1m 10m

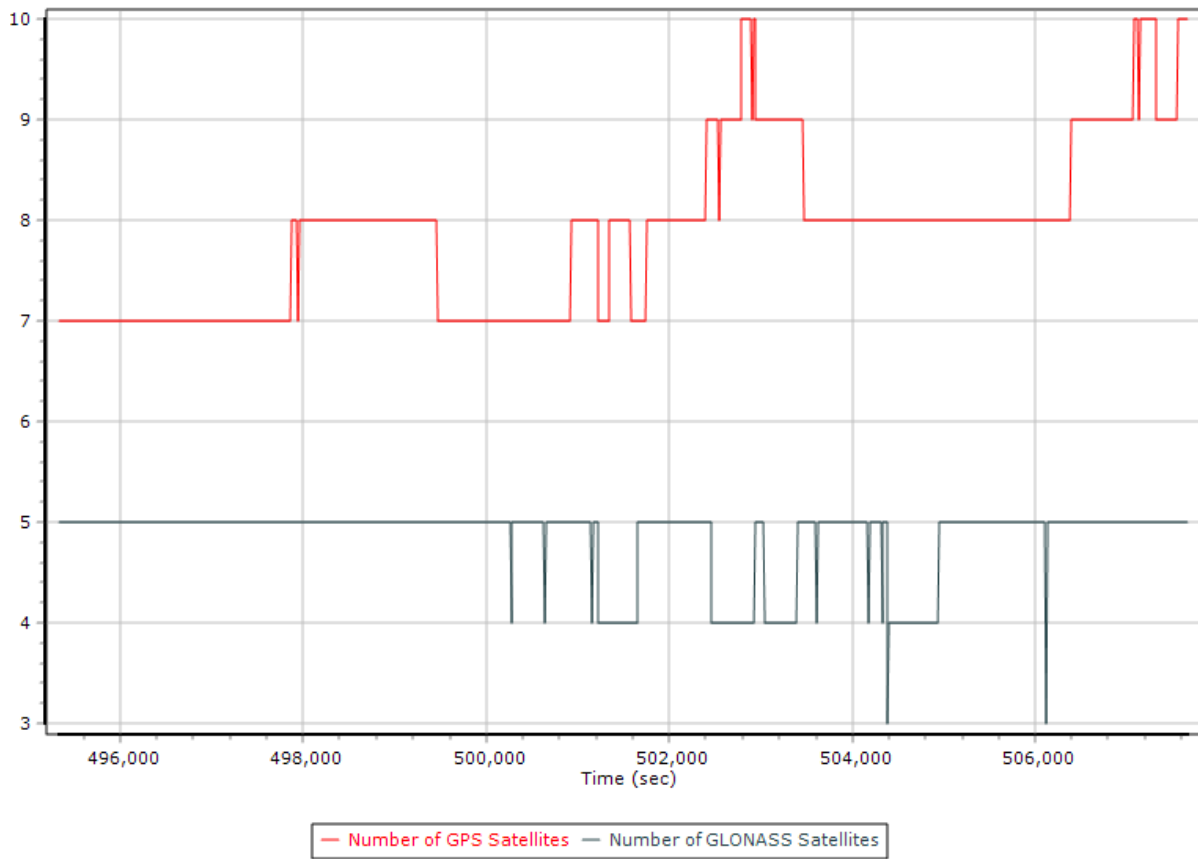
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

OK Cancel

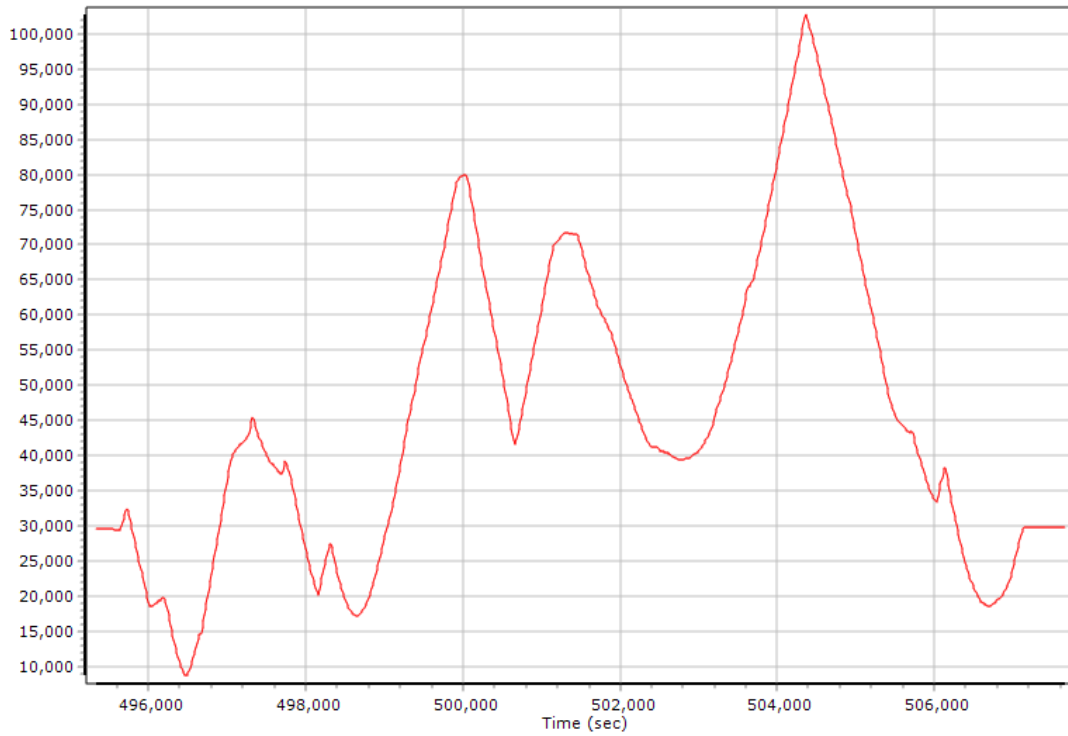




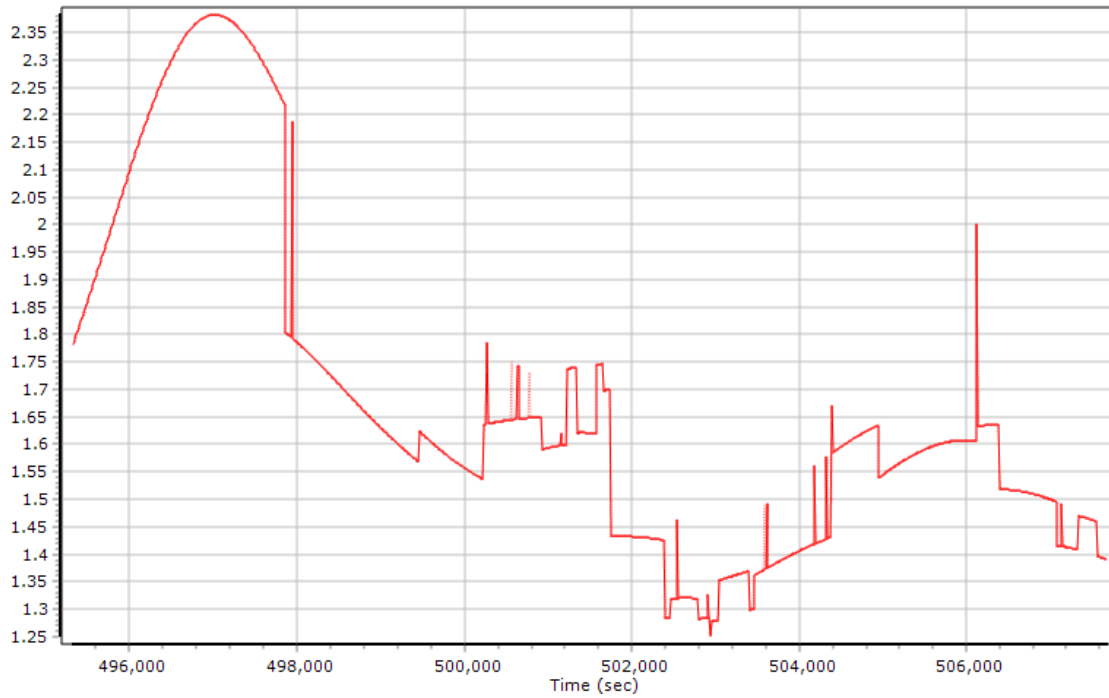




Baseline Length(m)

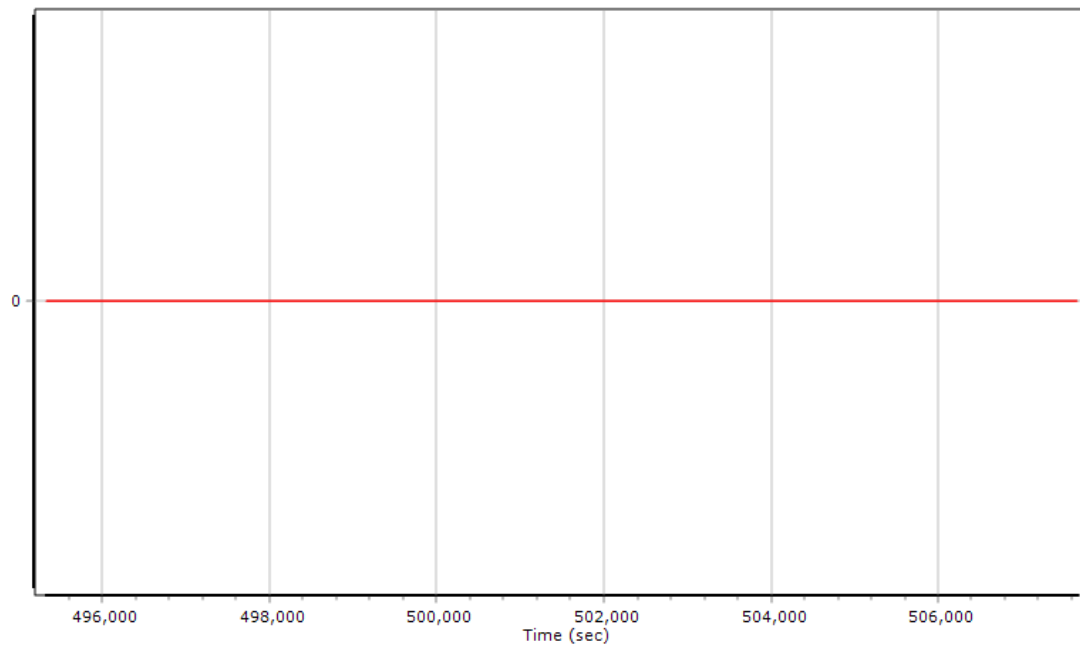


PDOP



Forward Reverse

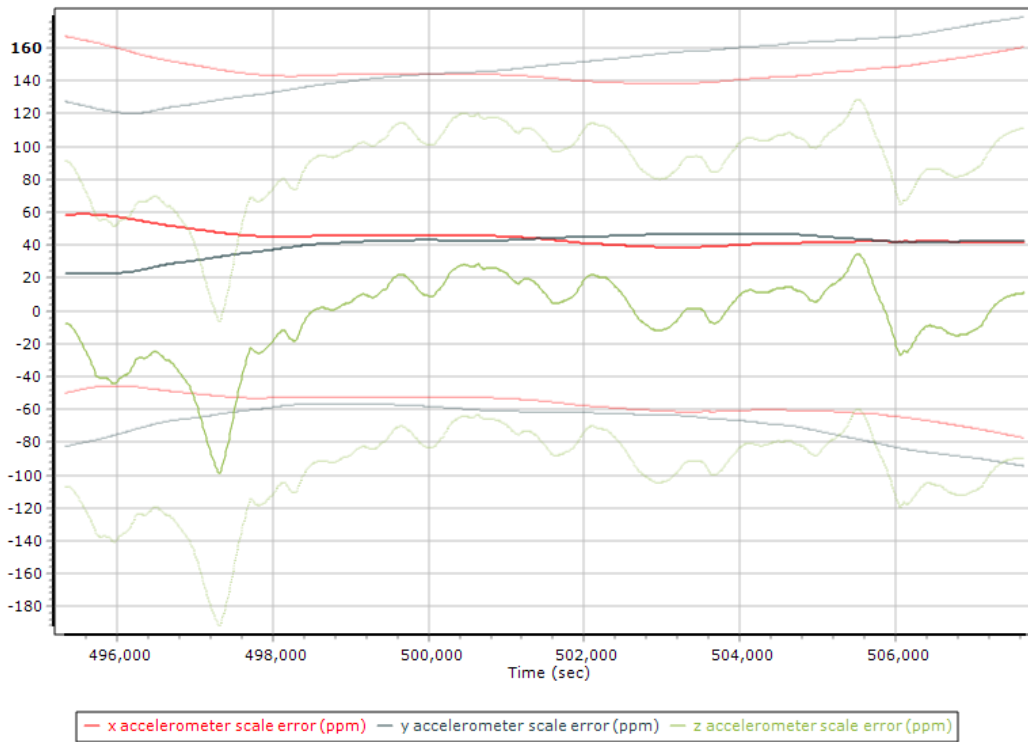
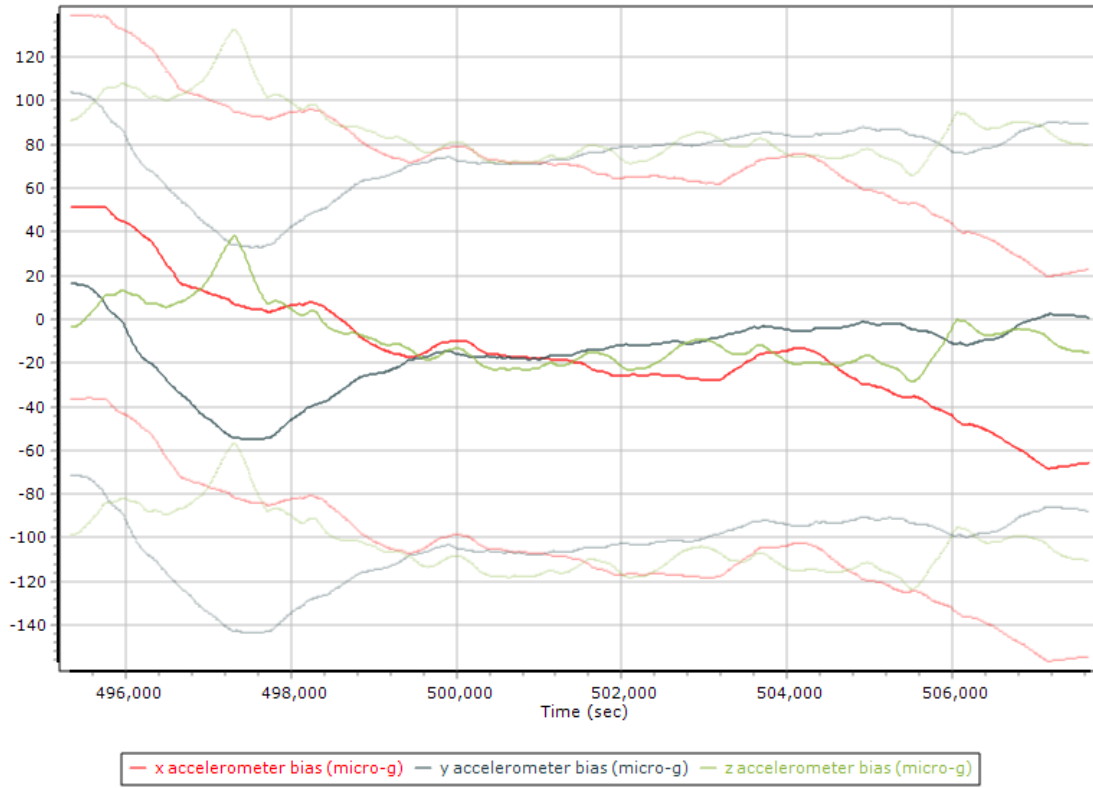
Processing Mode

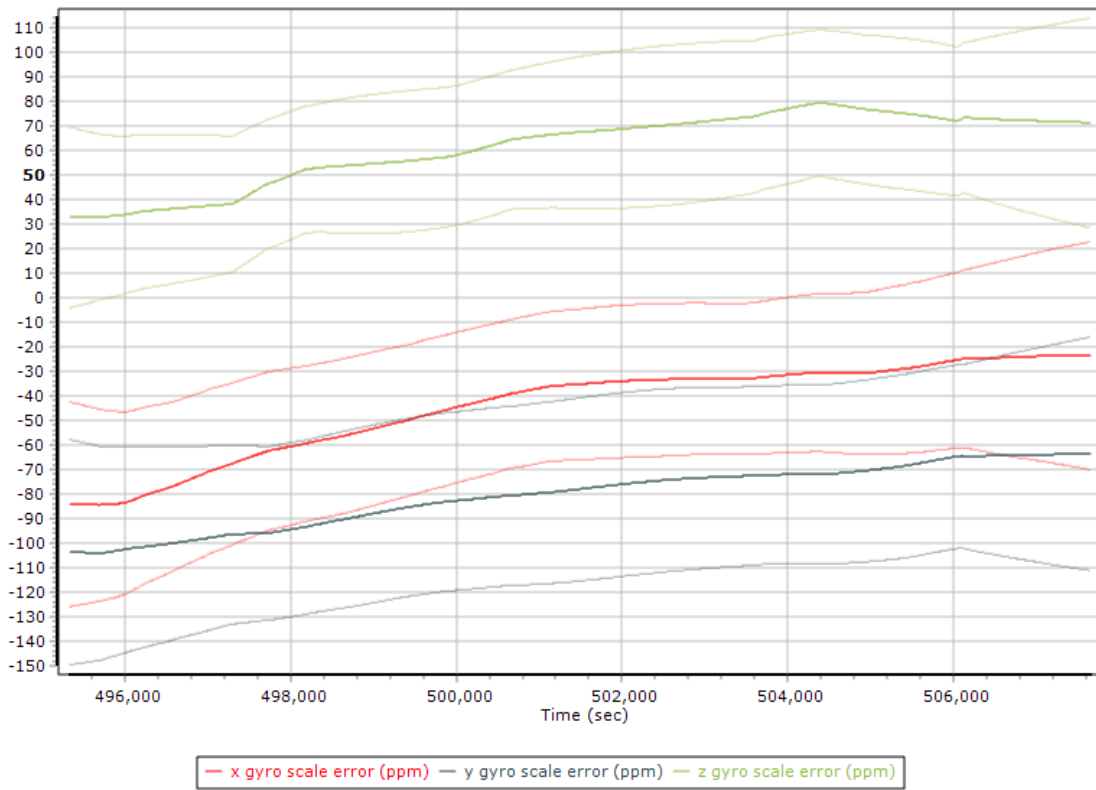
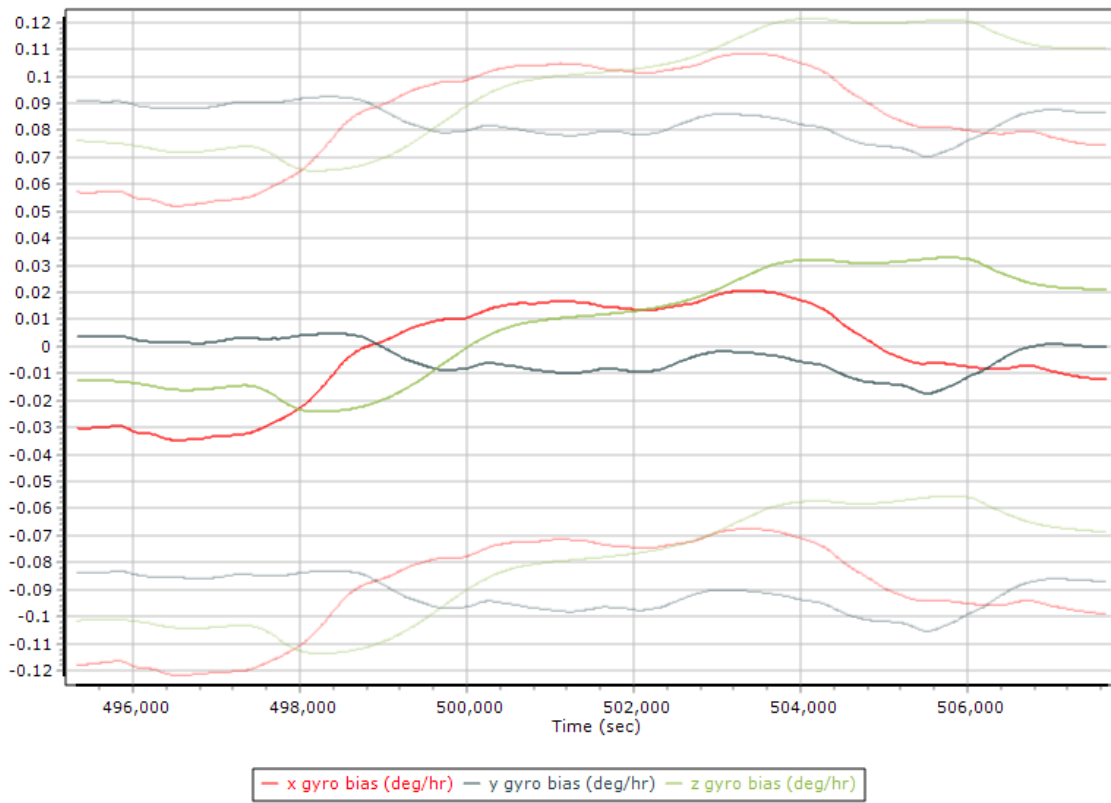


Forward Reverse

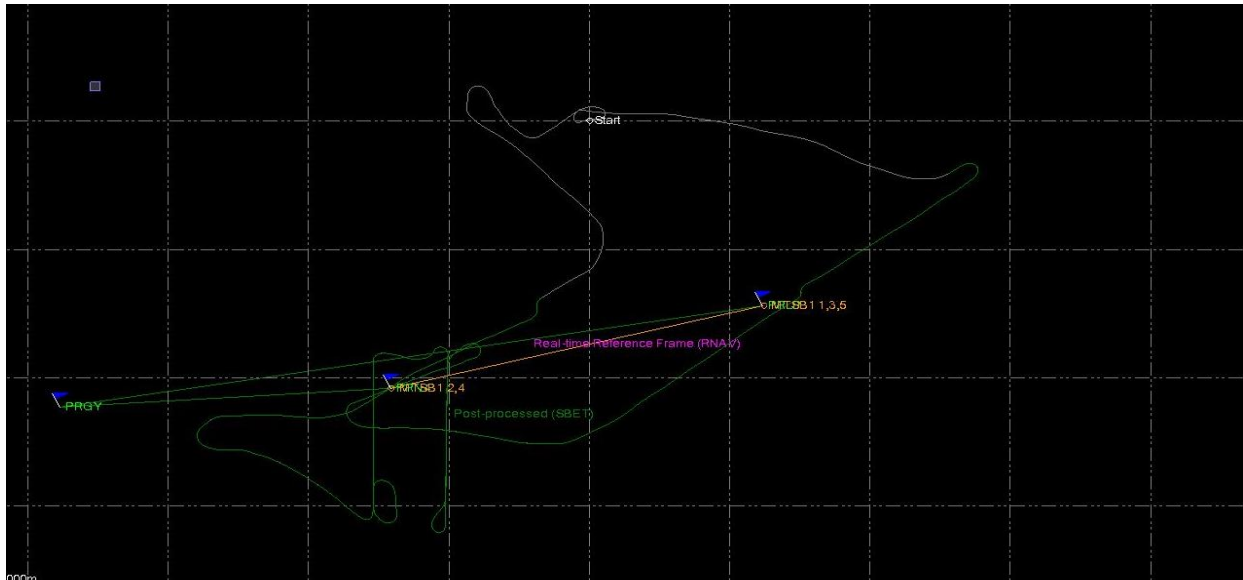
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





45A18301A_2



Project Settings

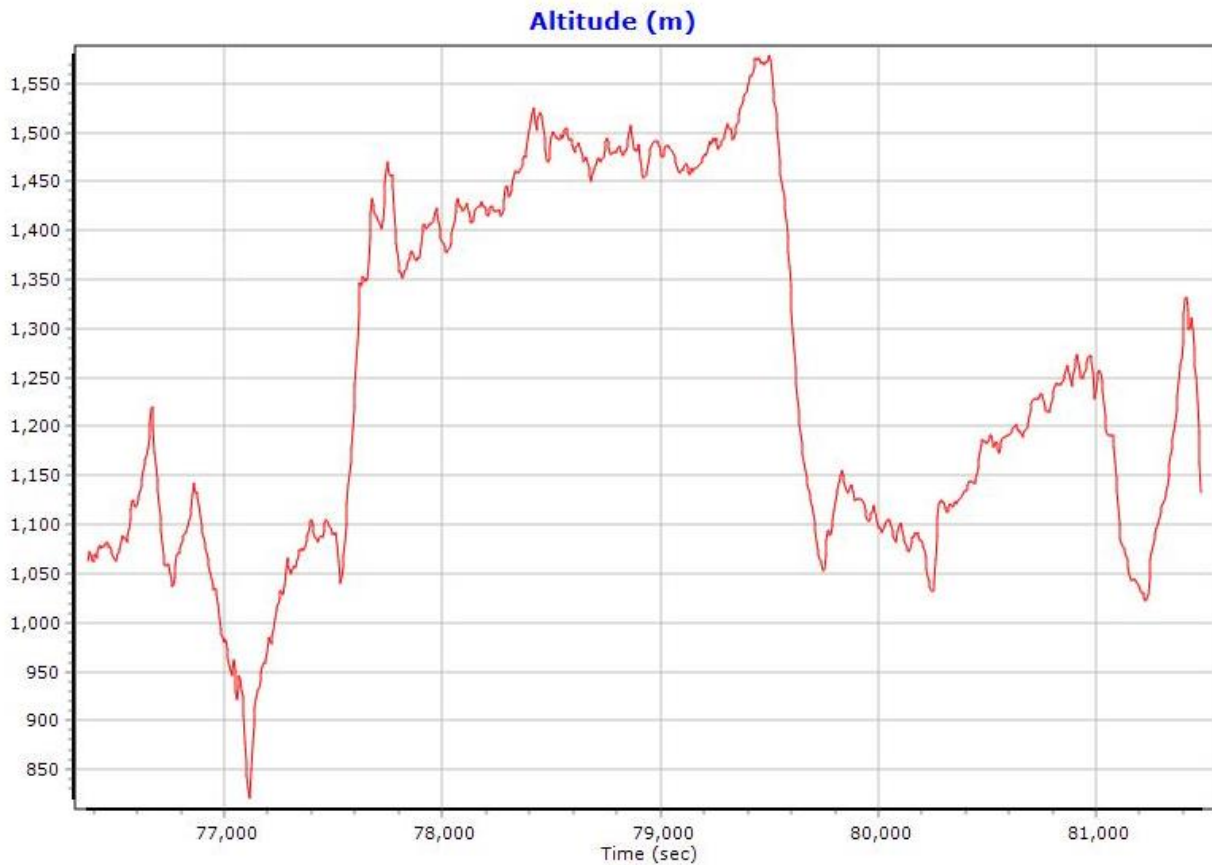
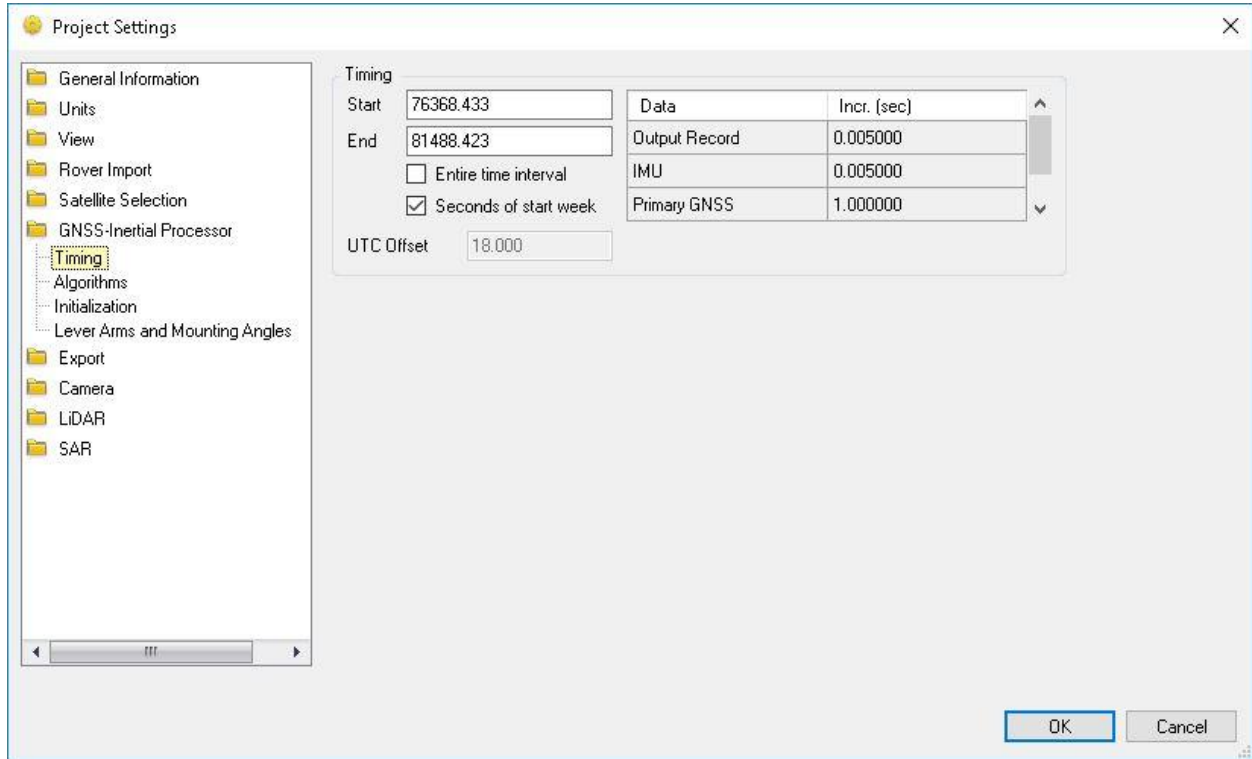
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LIDAR
- SAR

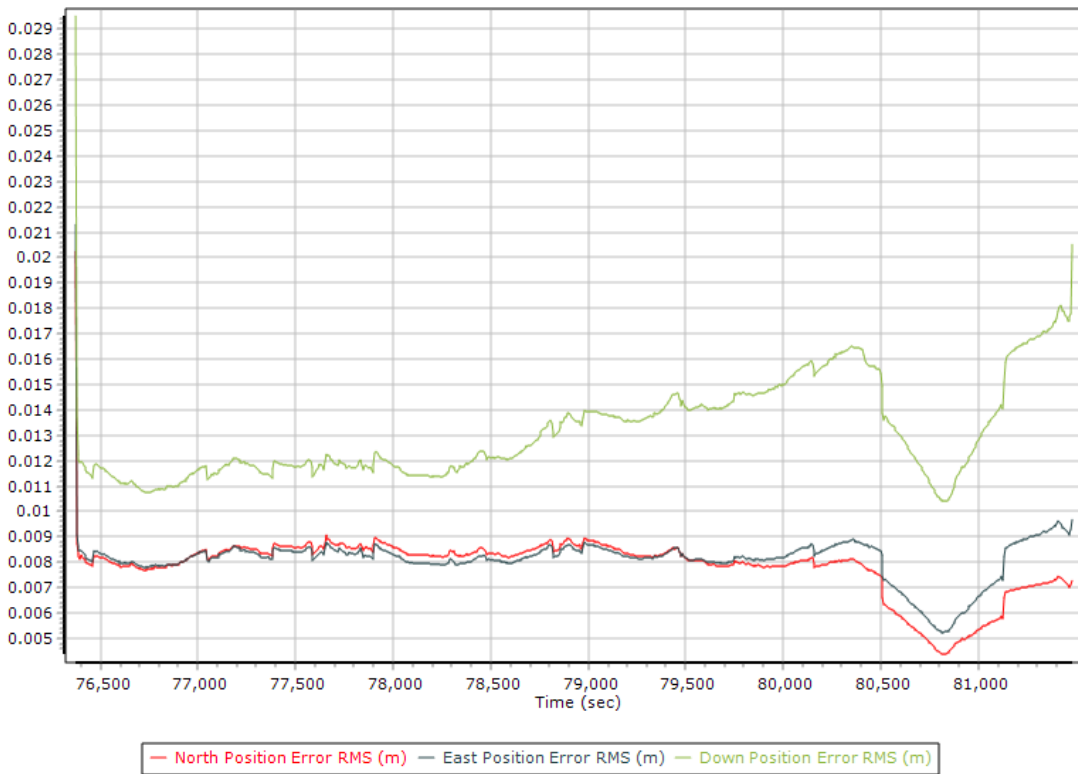
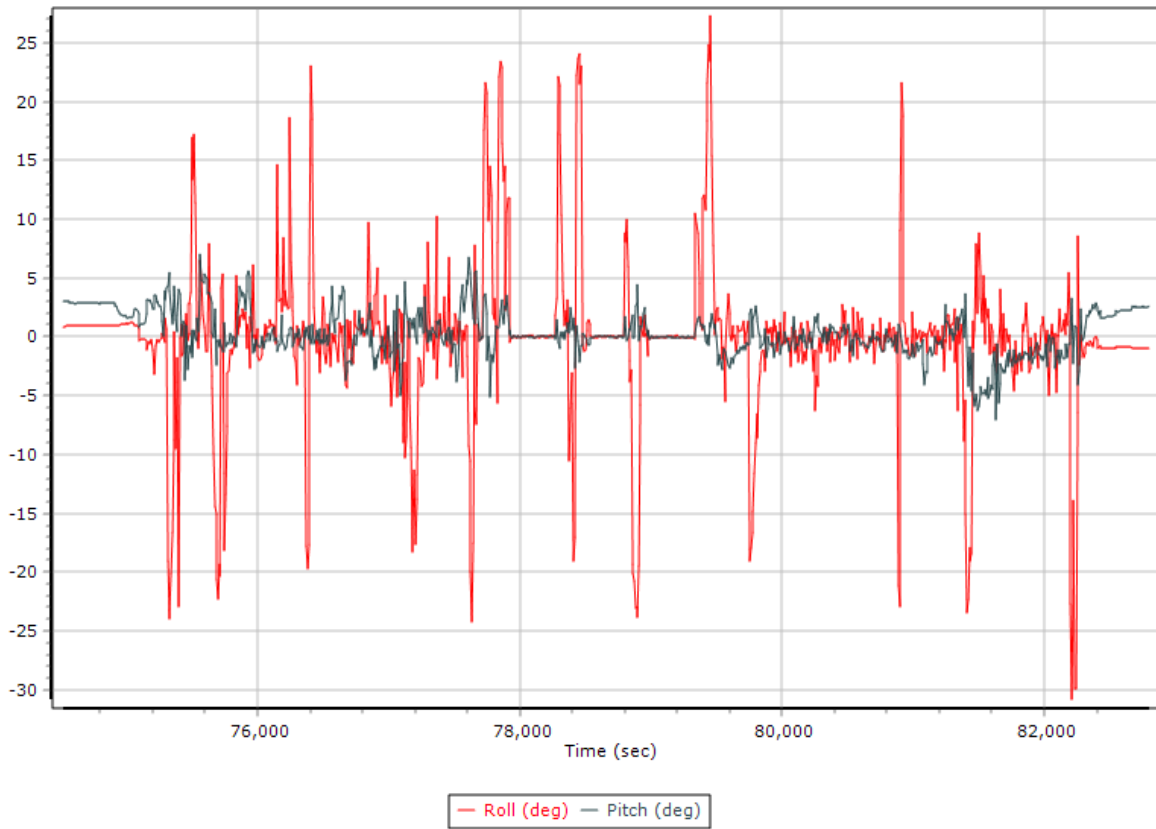
Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.049 m	0.003 m	-1.230 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

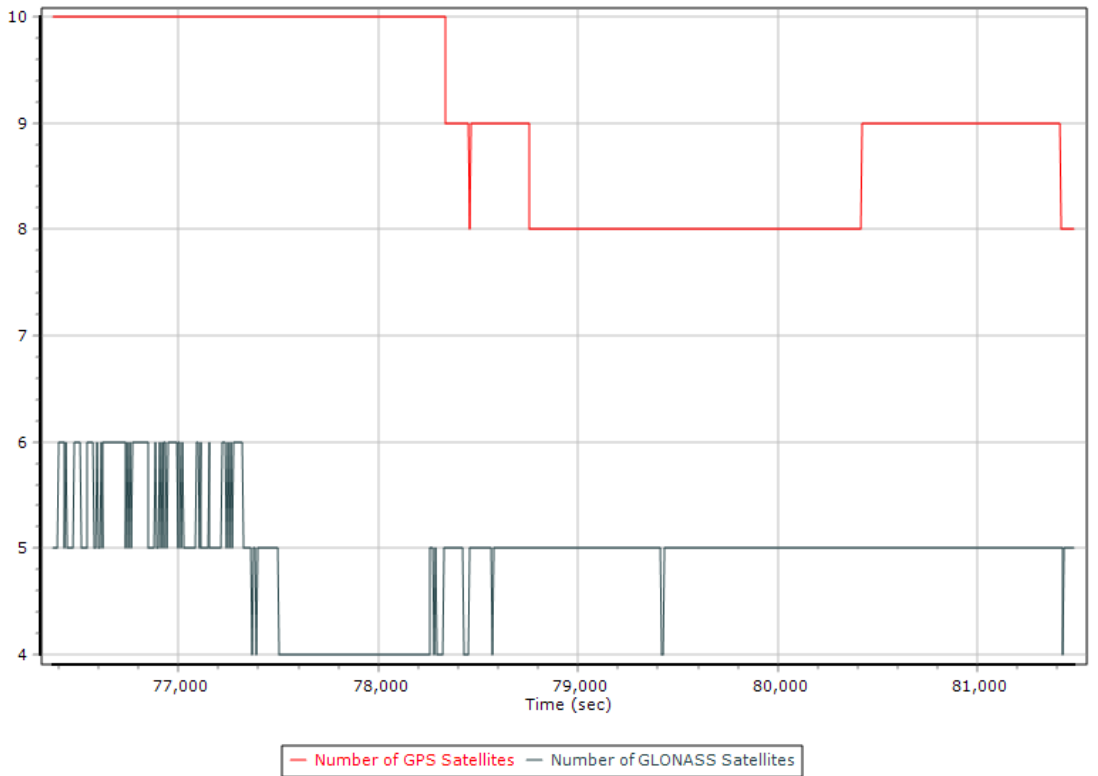
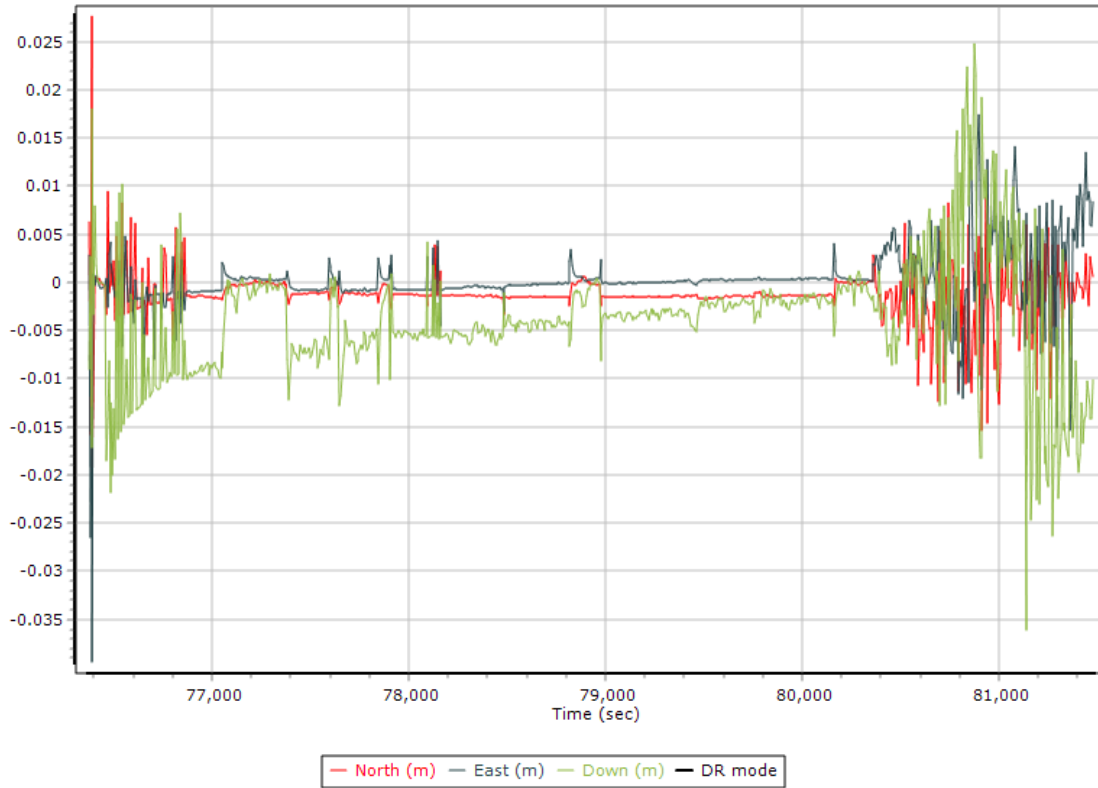
Standard Deviation: <3cm 10cm 50cm 1m 10m

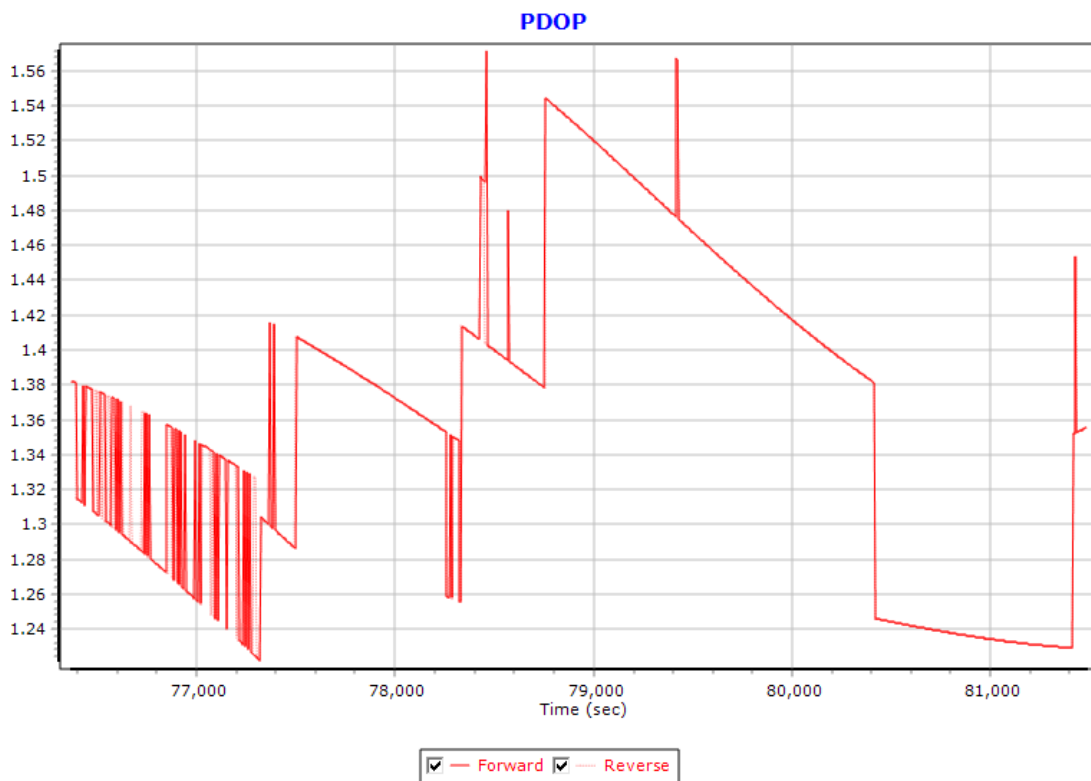
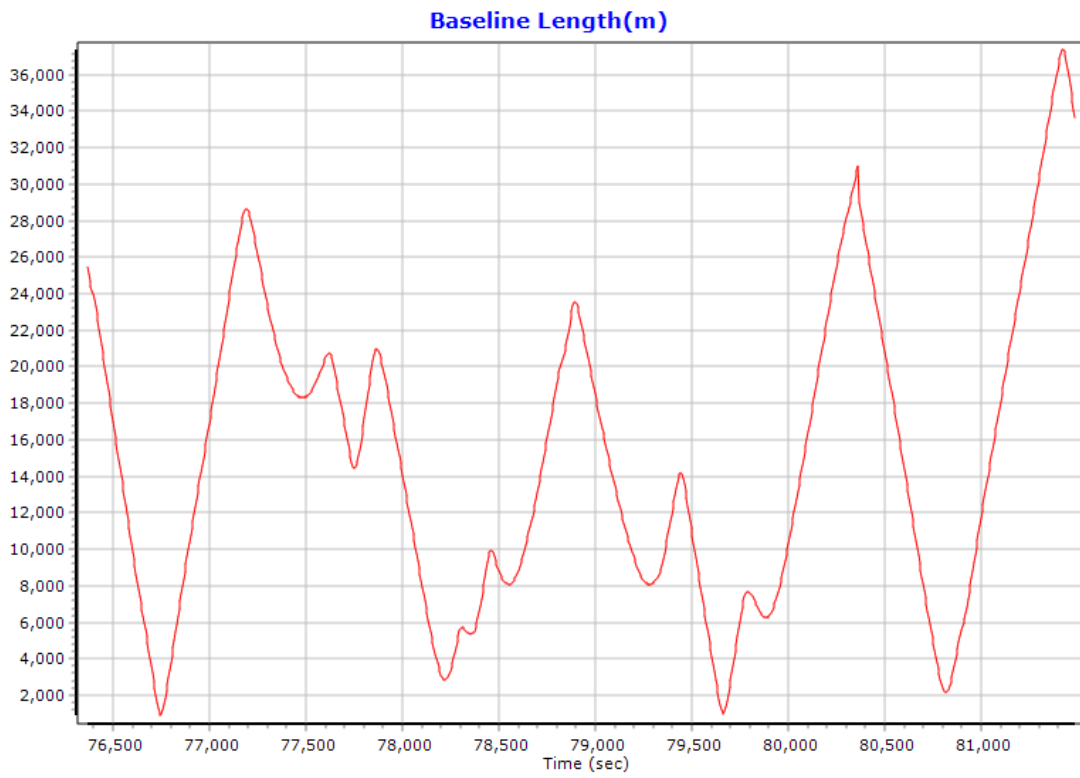
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

OK Cancel

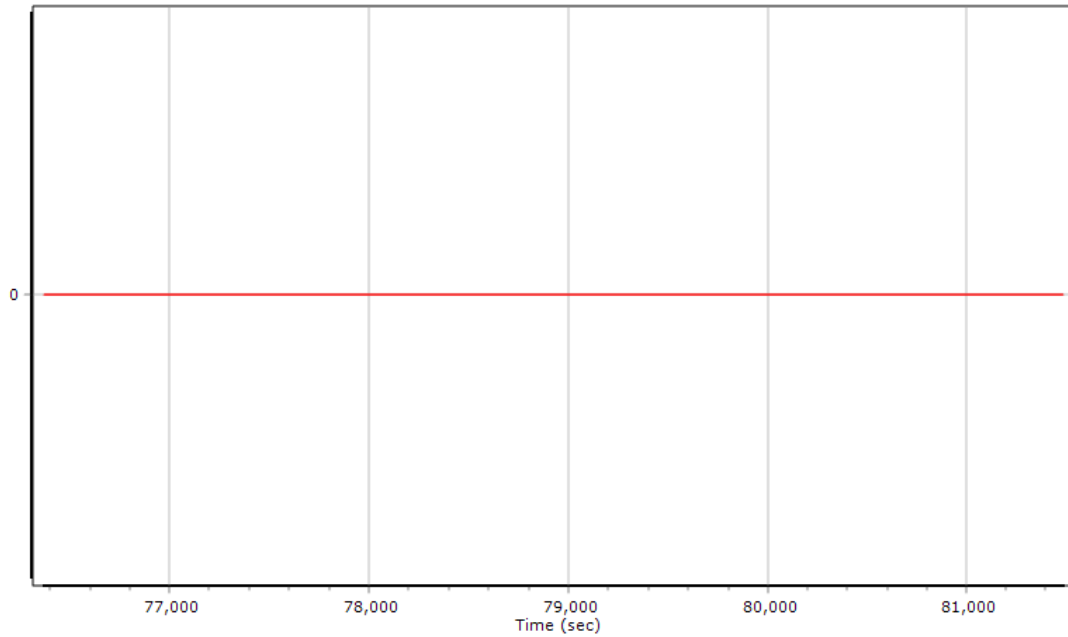








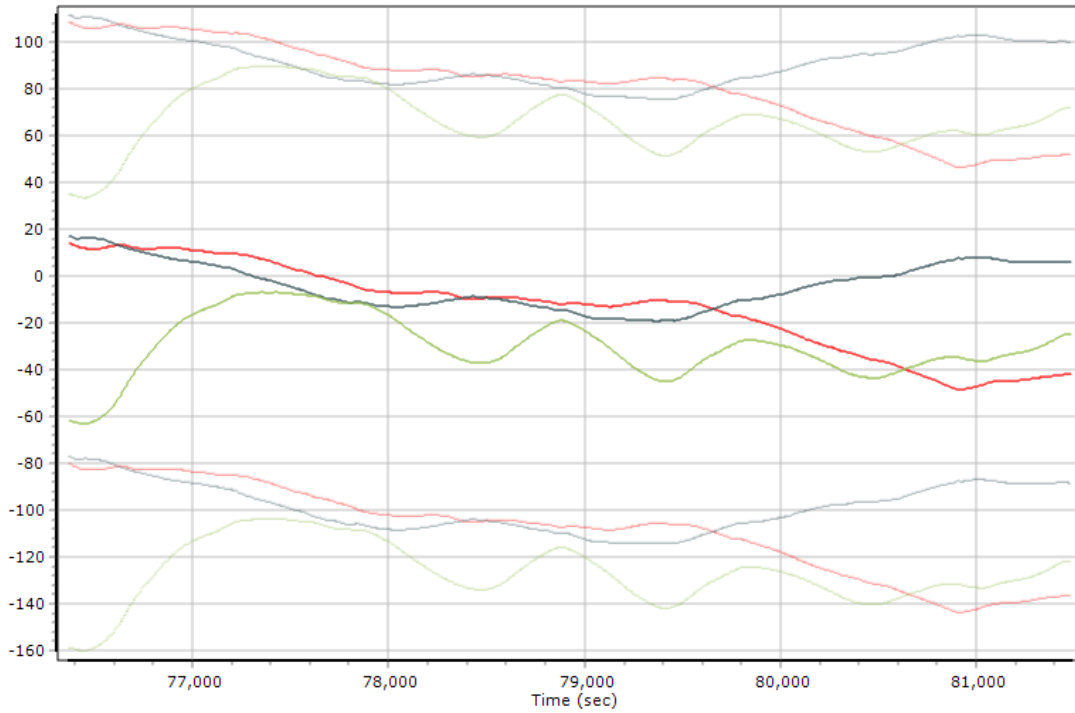
Processing Mode



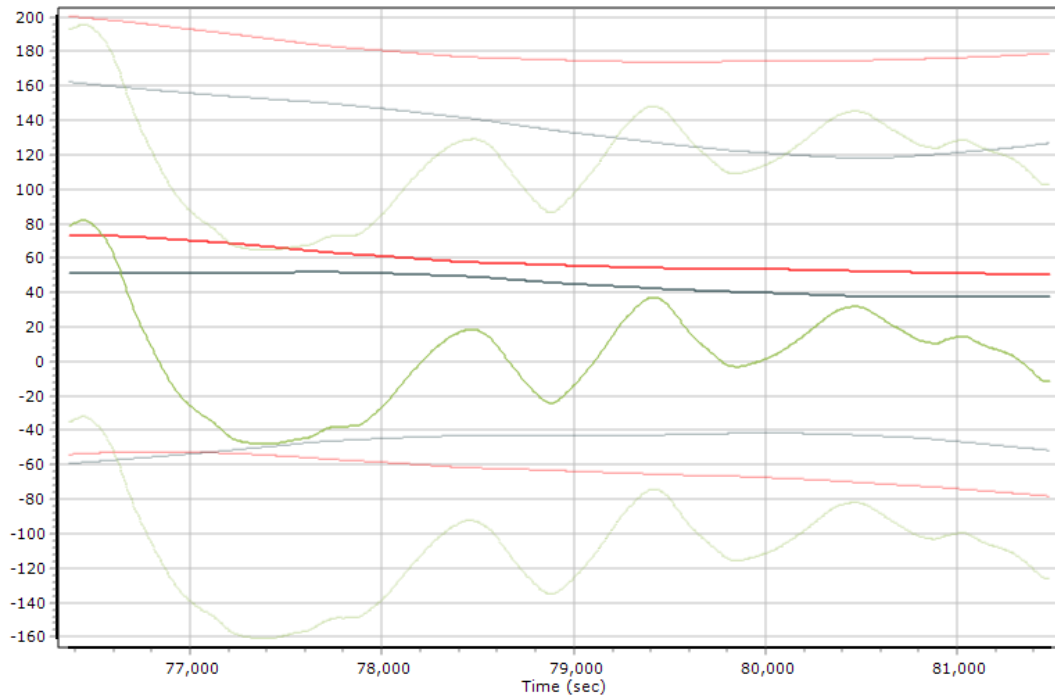
Forward Reverse

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

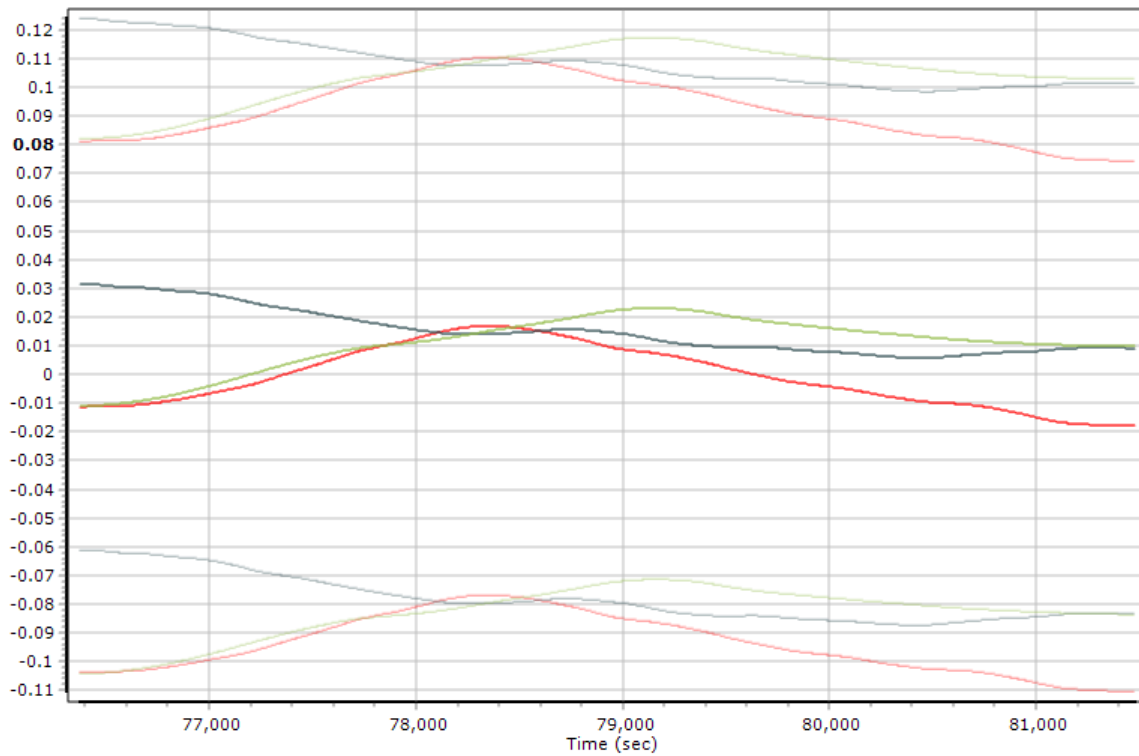
Sensor Errors



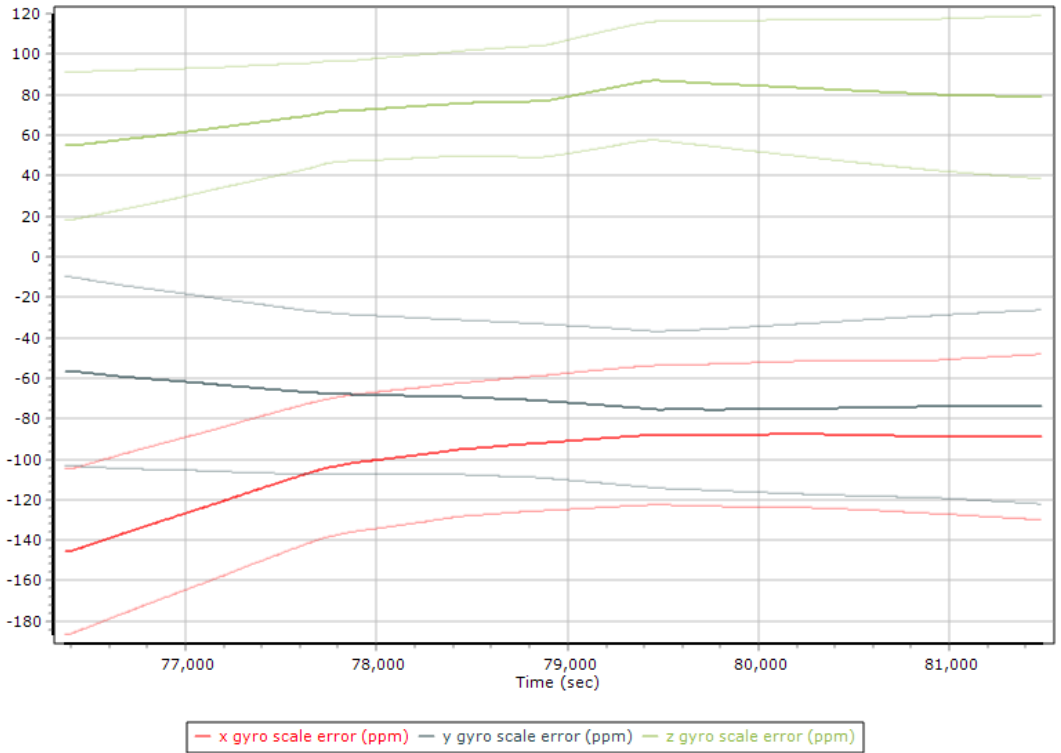
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



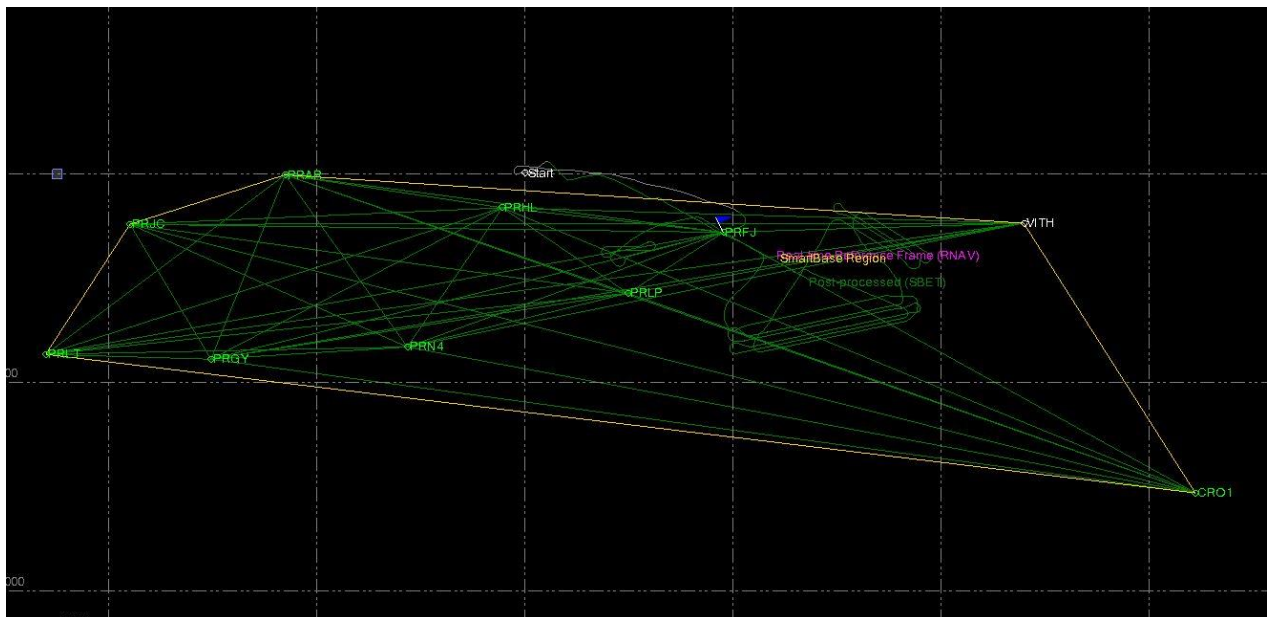
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

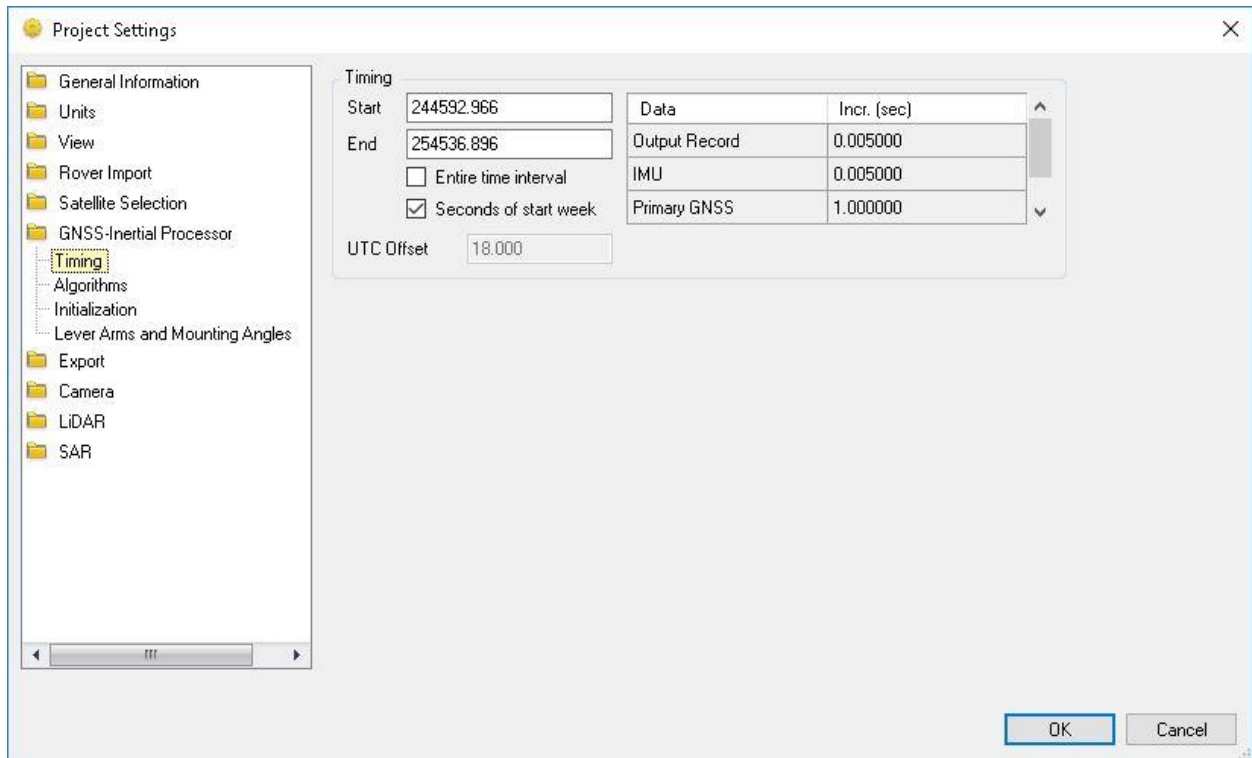
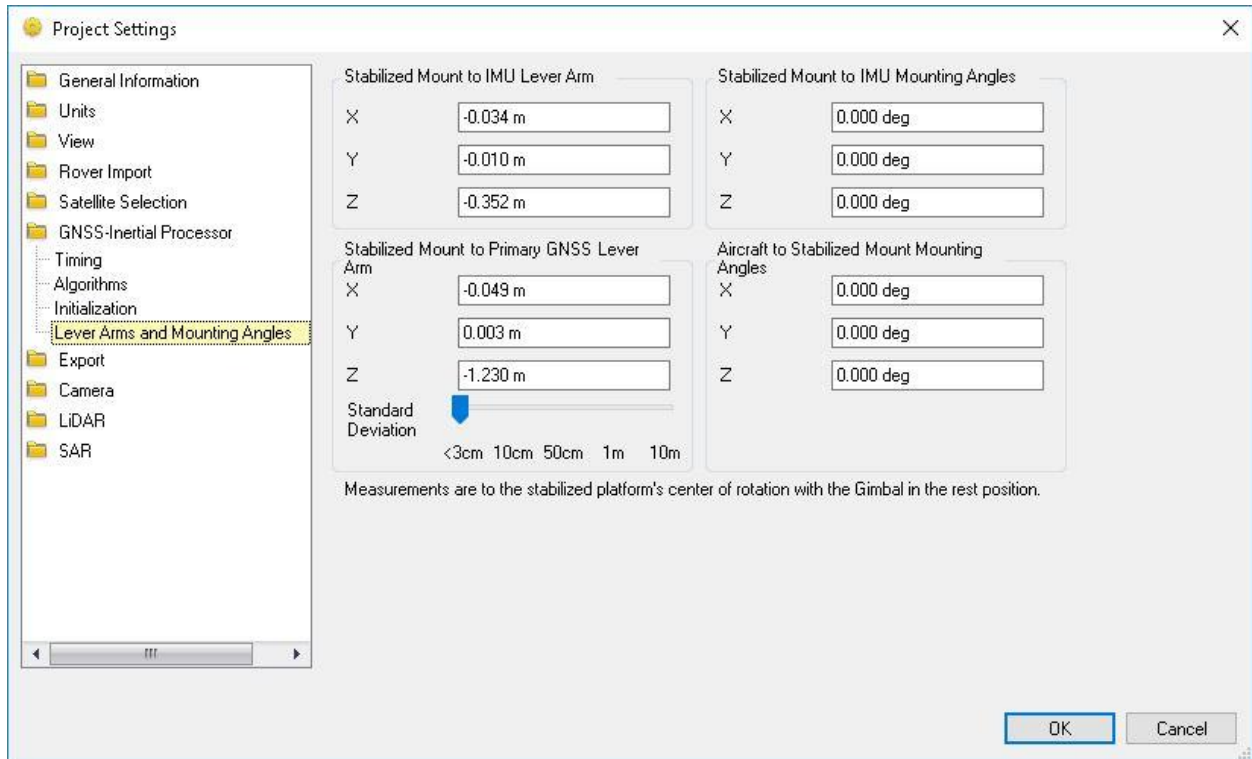


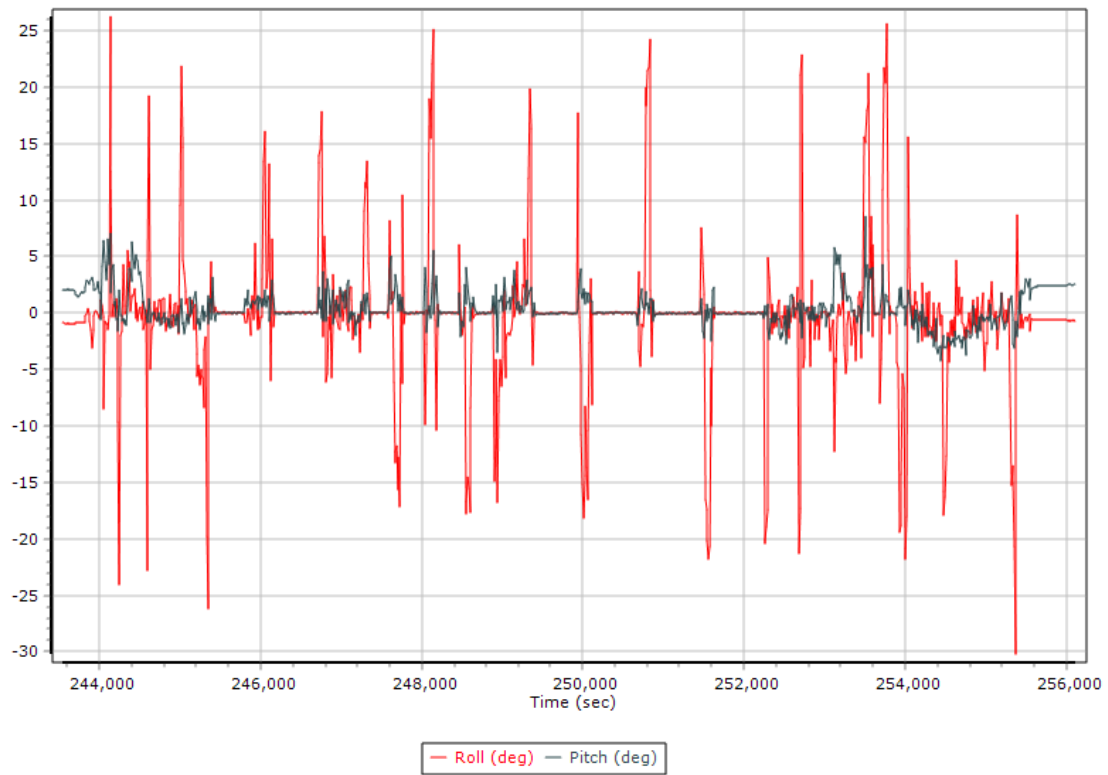
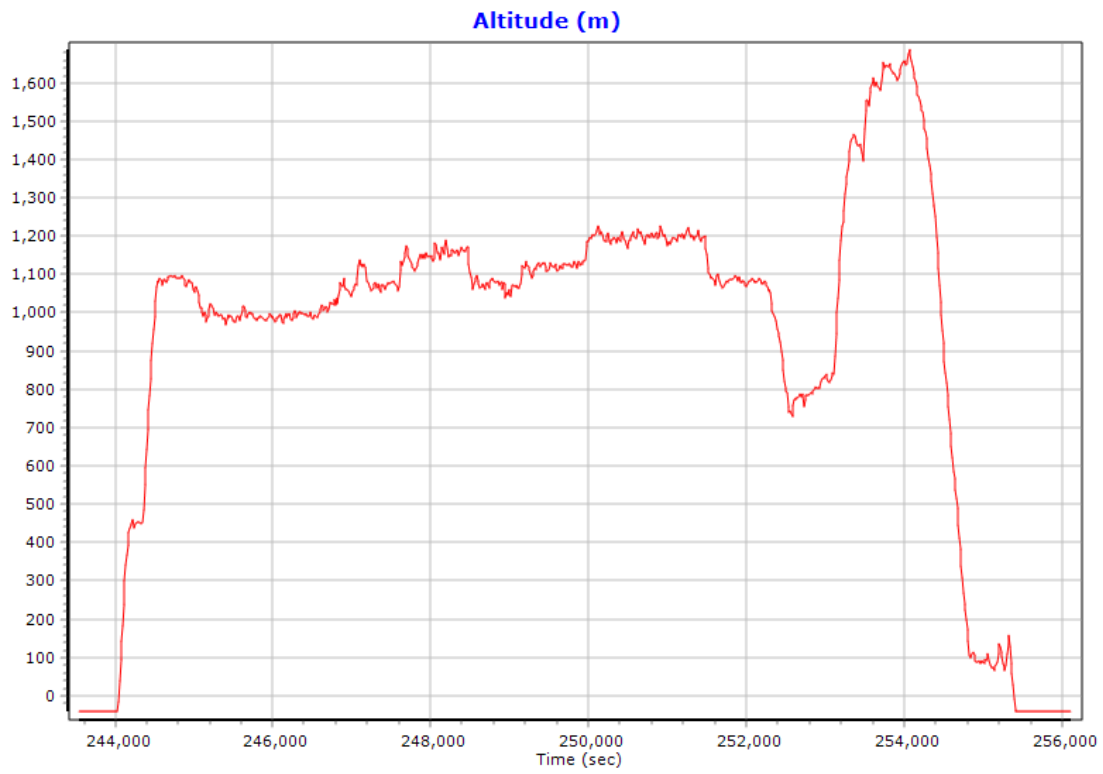
— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

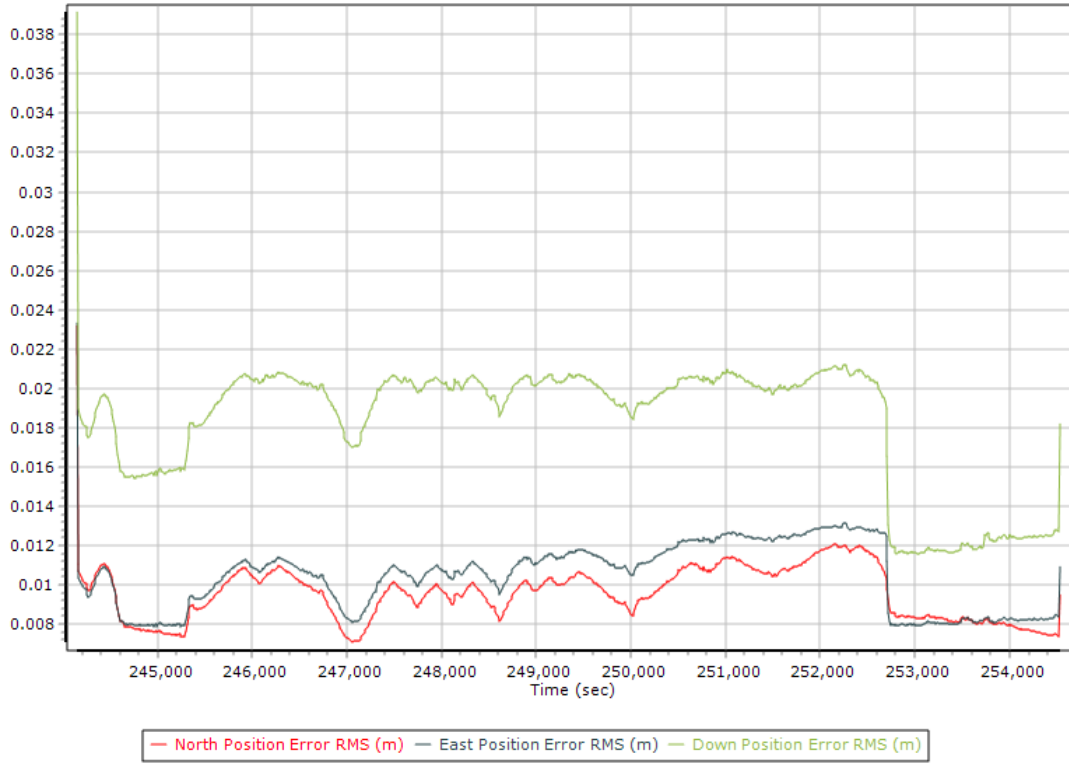


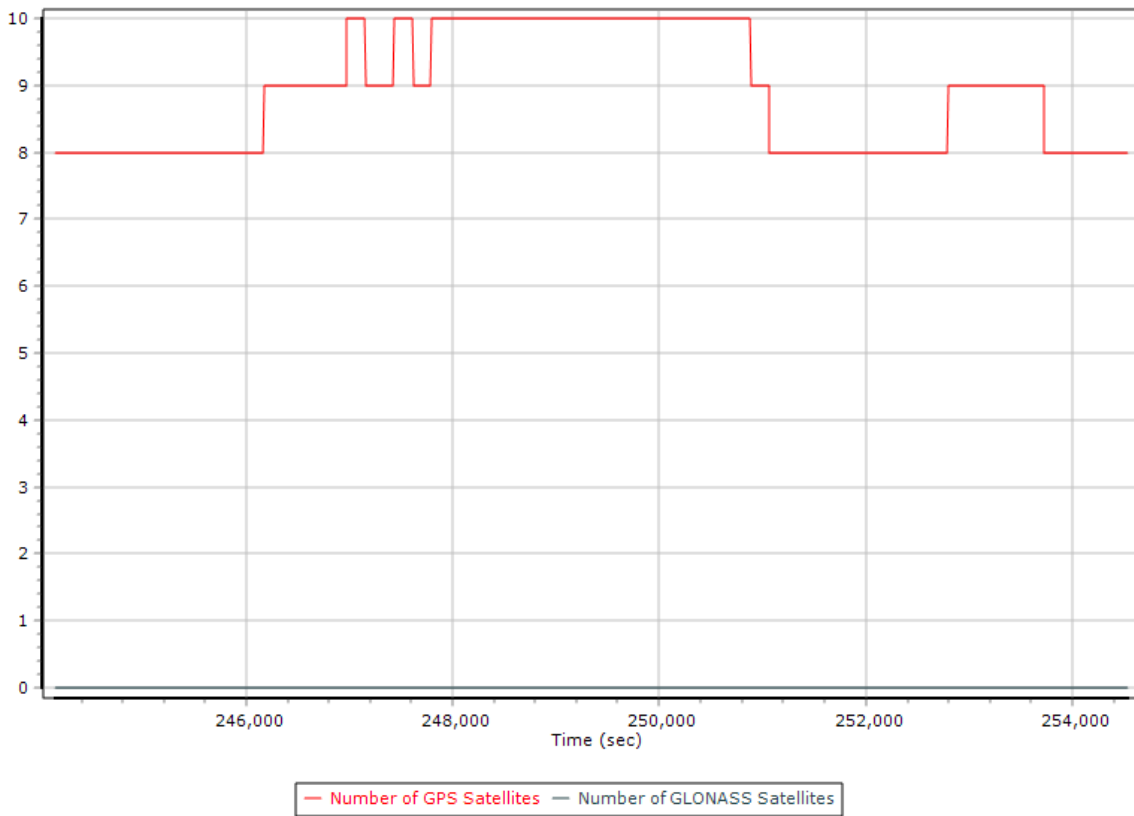
45A18303A



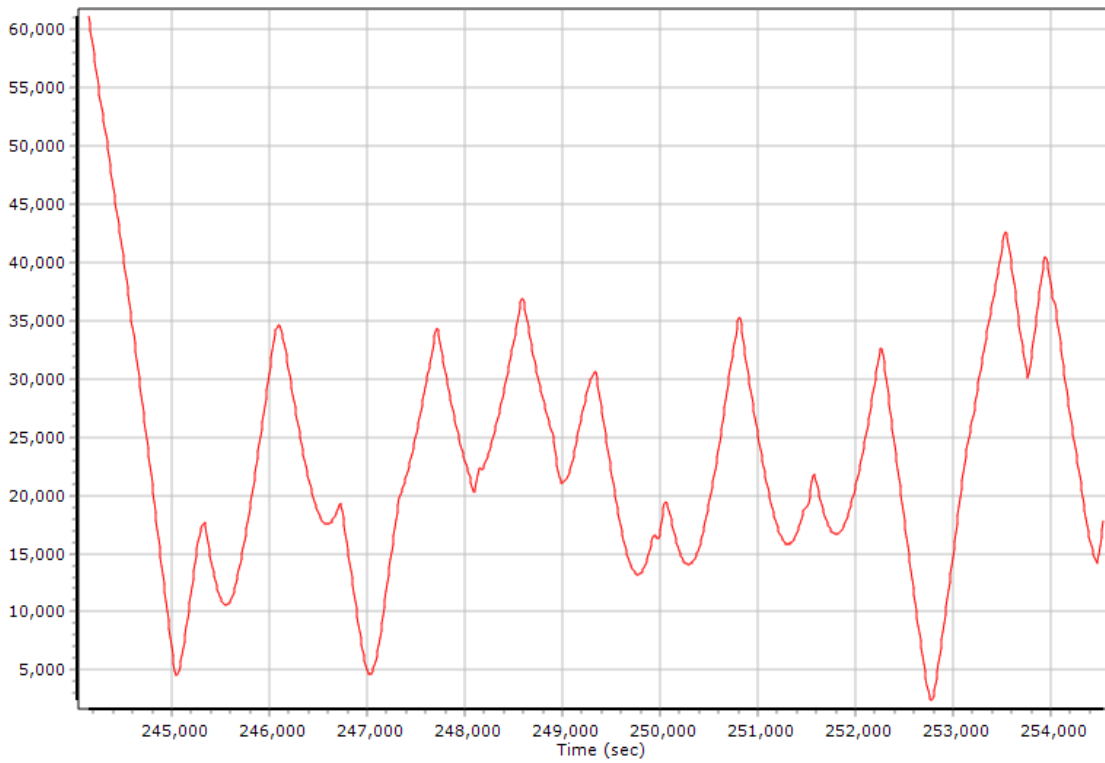




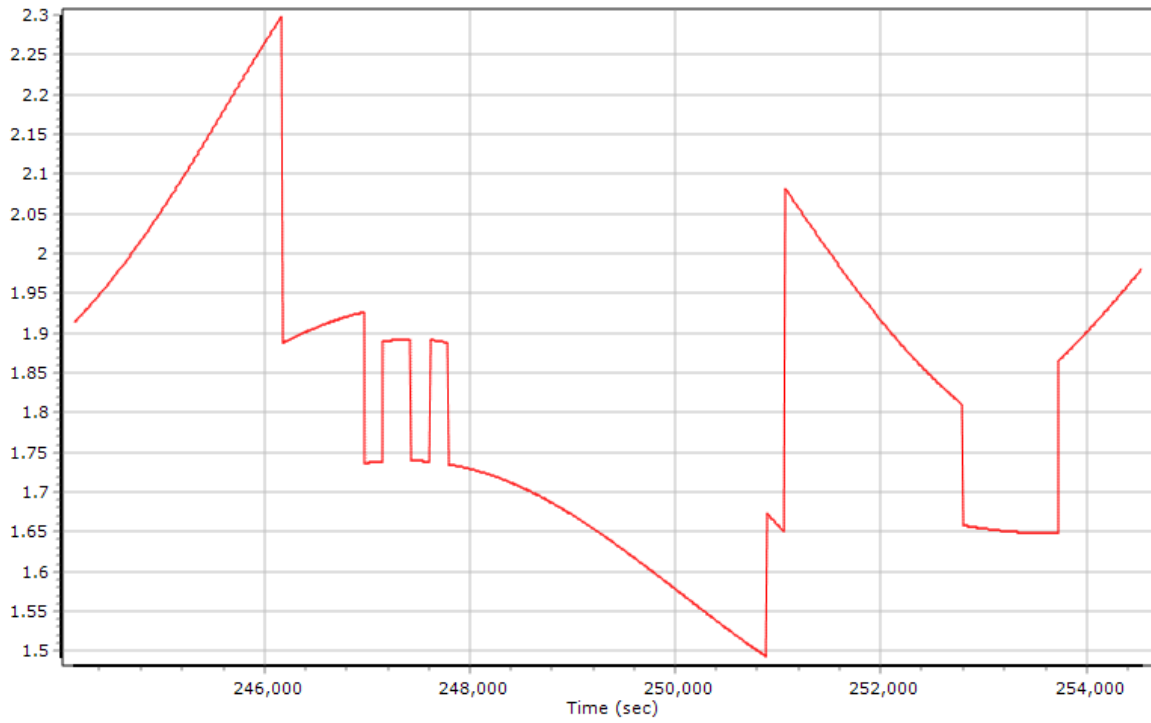




Baseline Length(m)

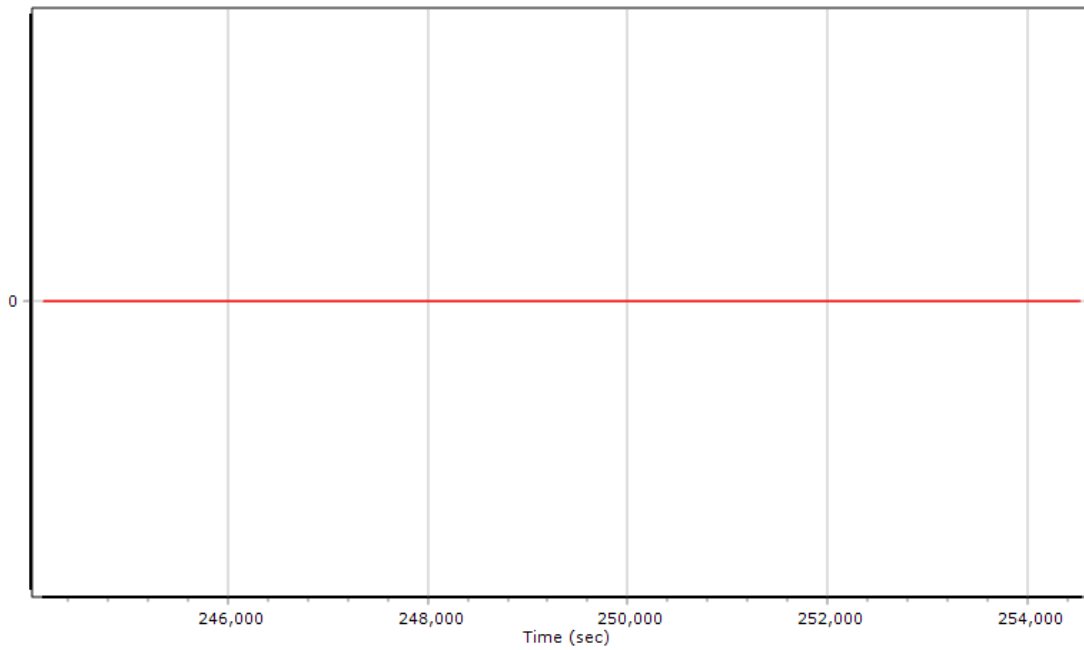


PDOP



Forward Reverse

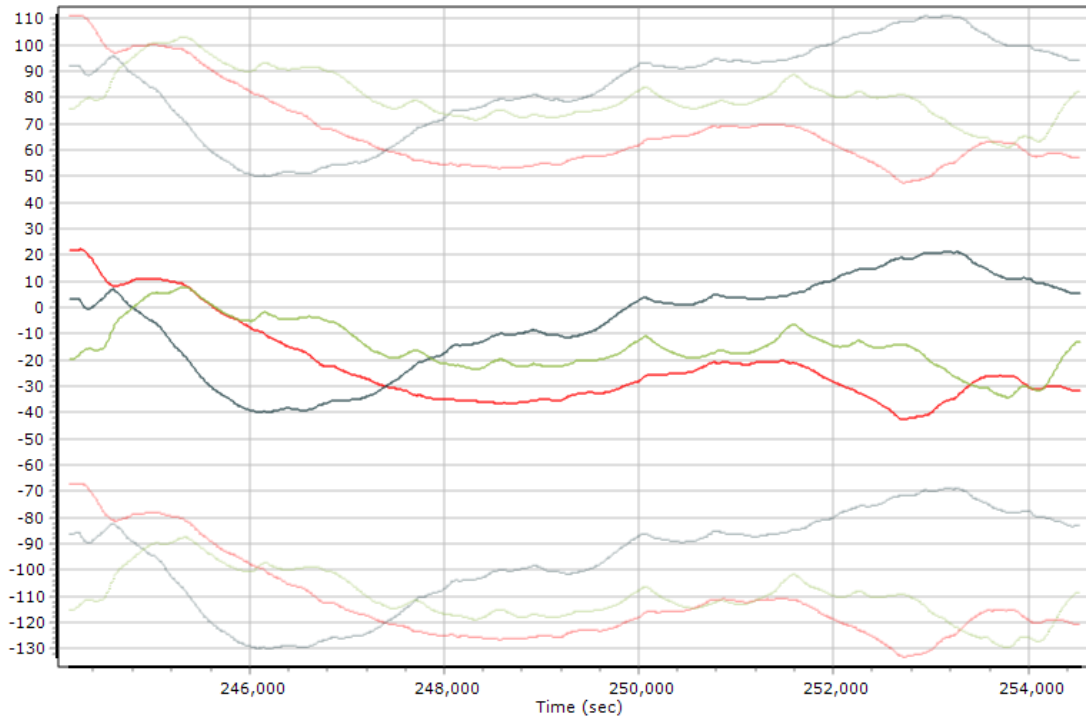
Processing Mode



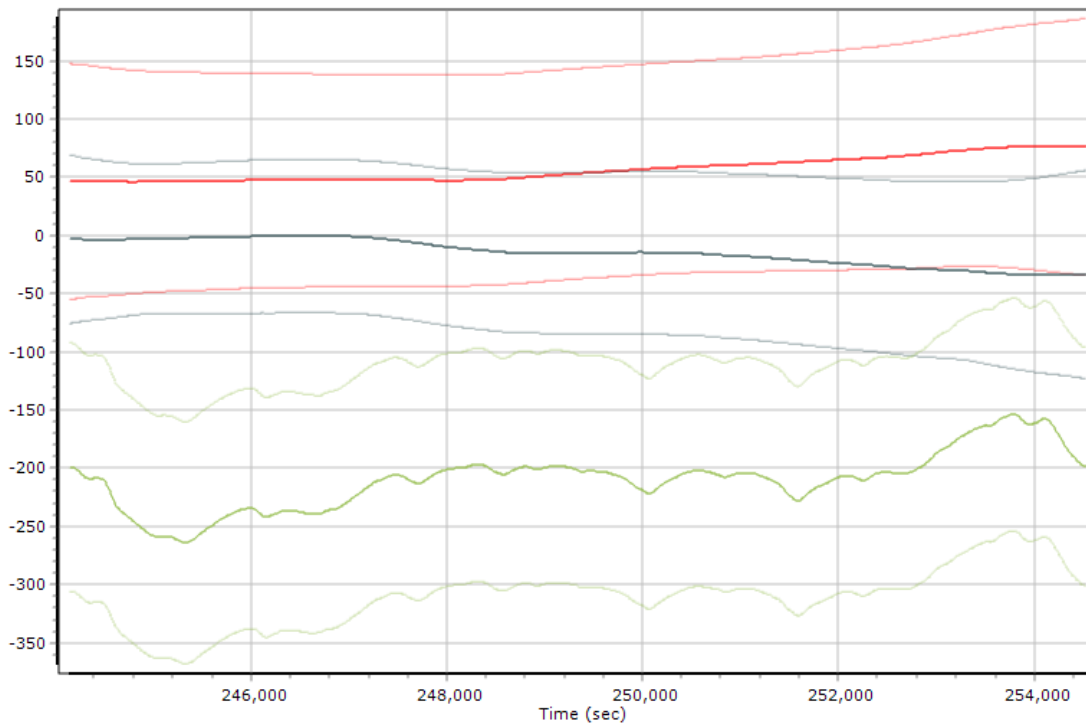
Forward Reverse

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

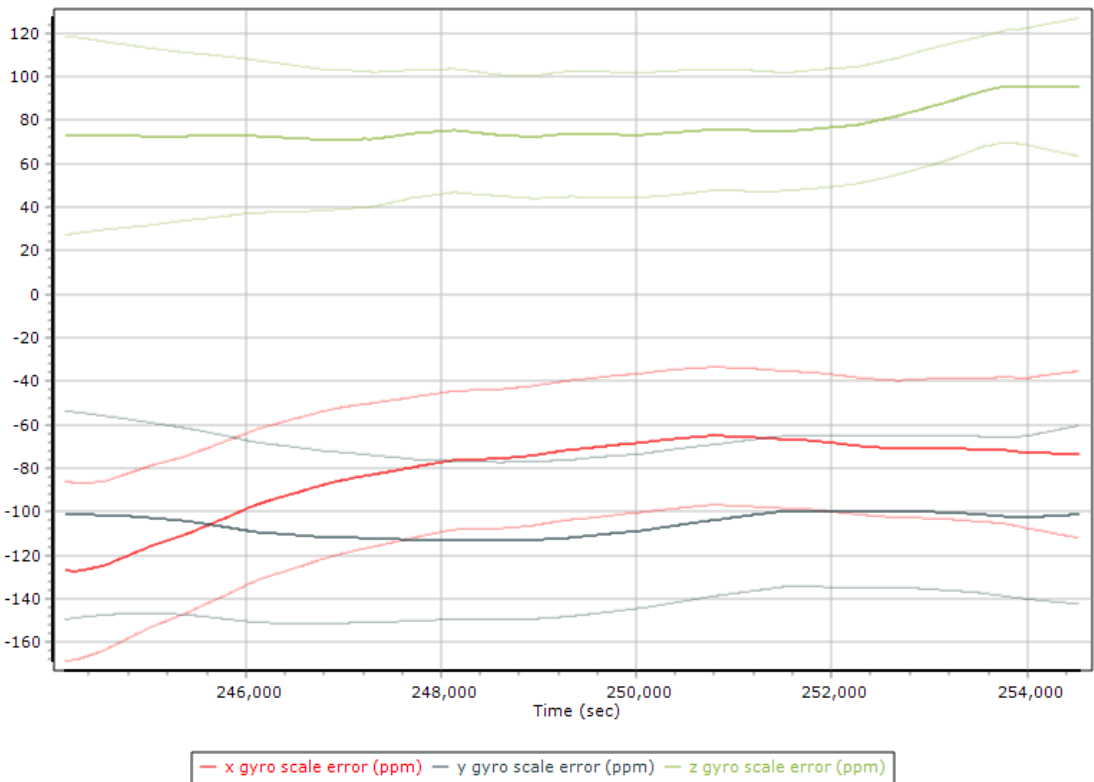
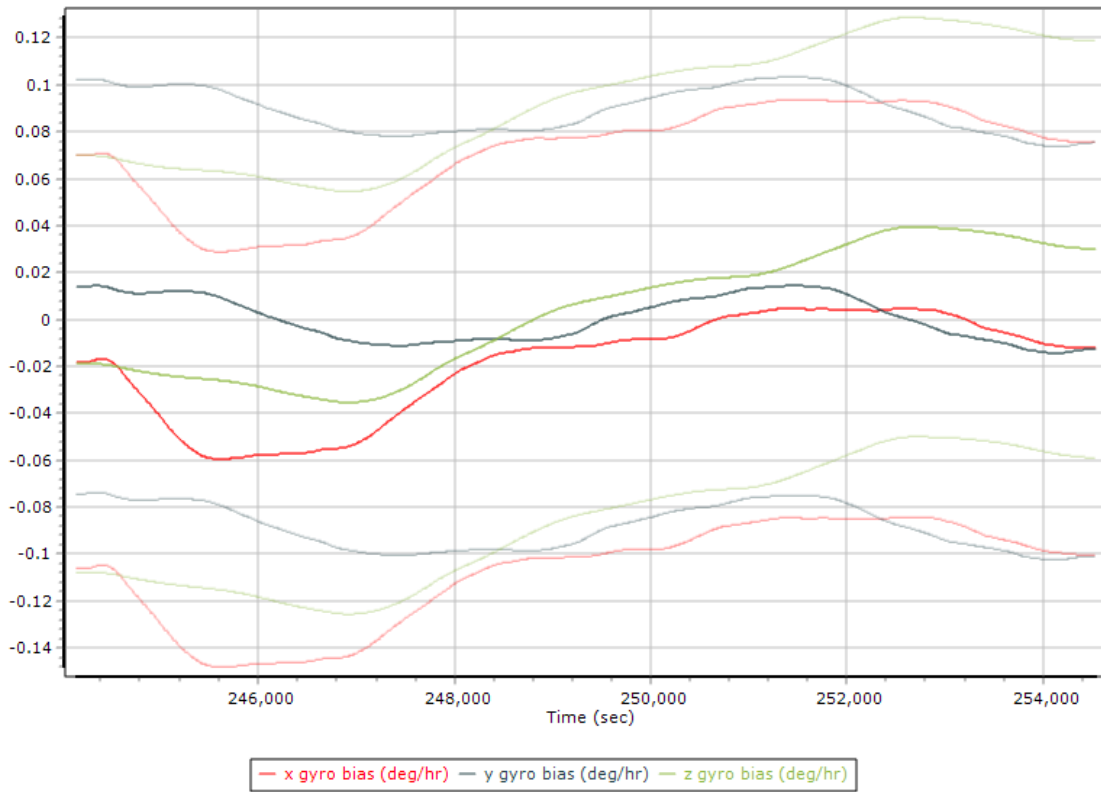
Sensor Errors



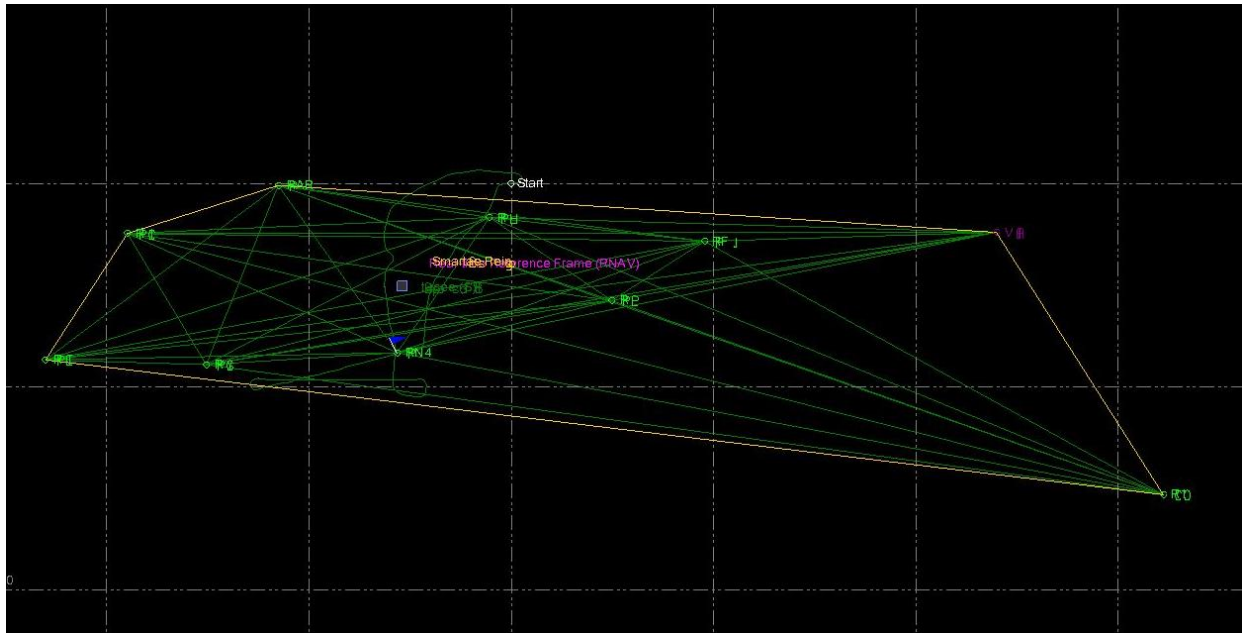
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



45A18313A



Project Settings

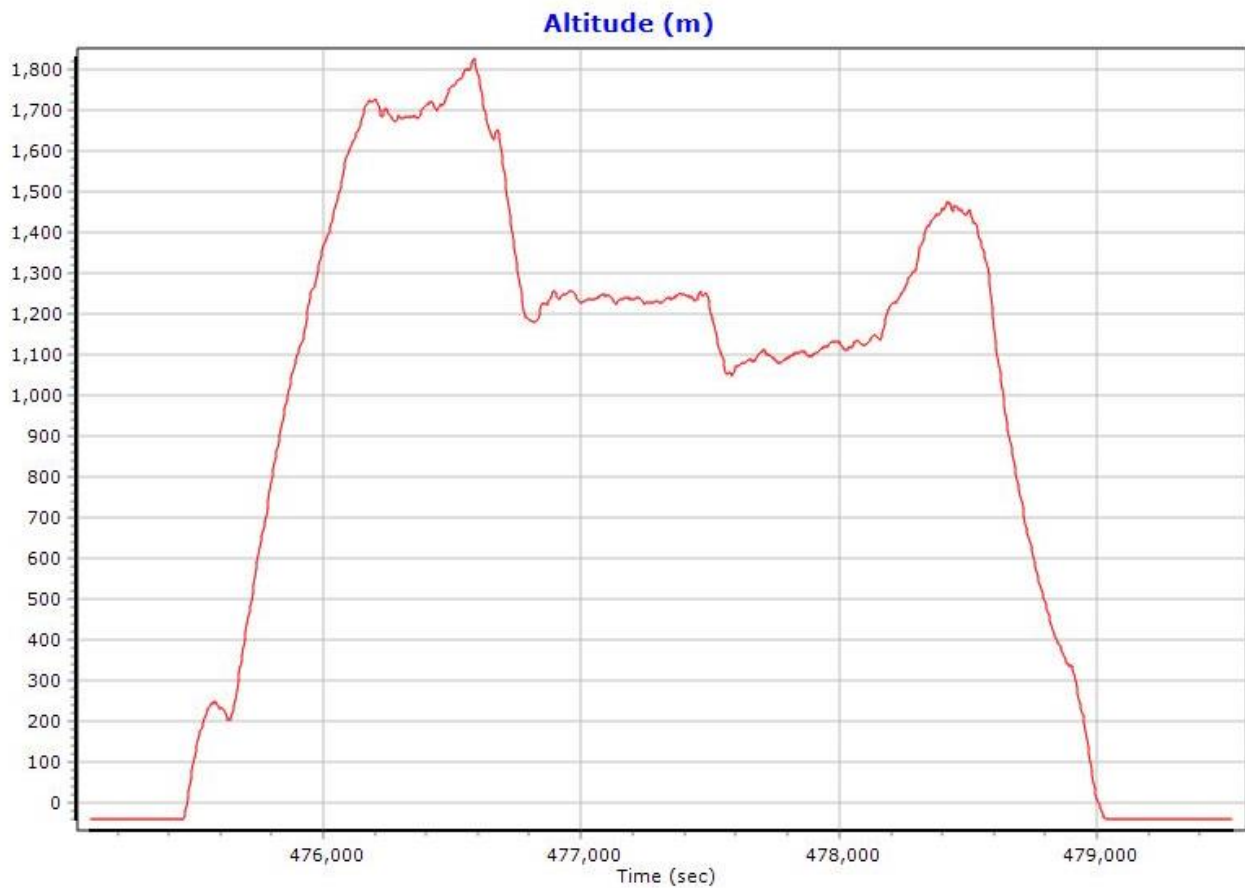
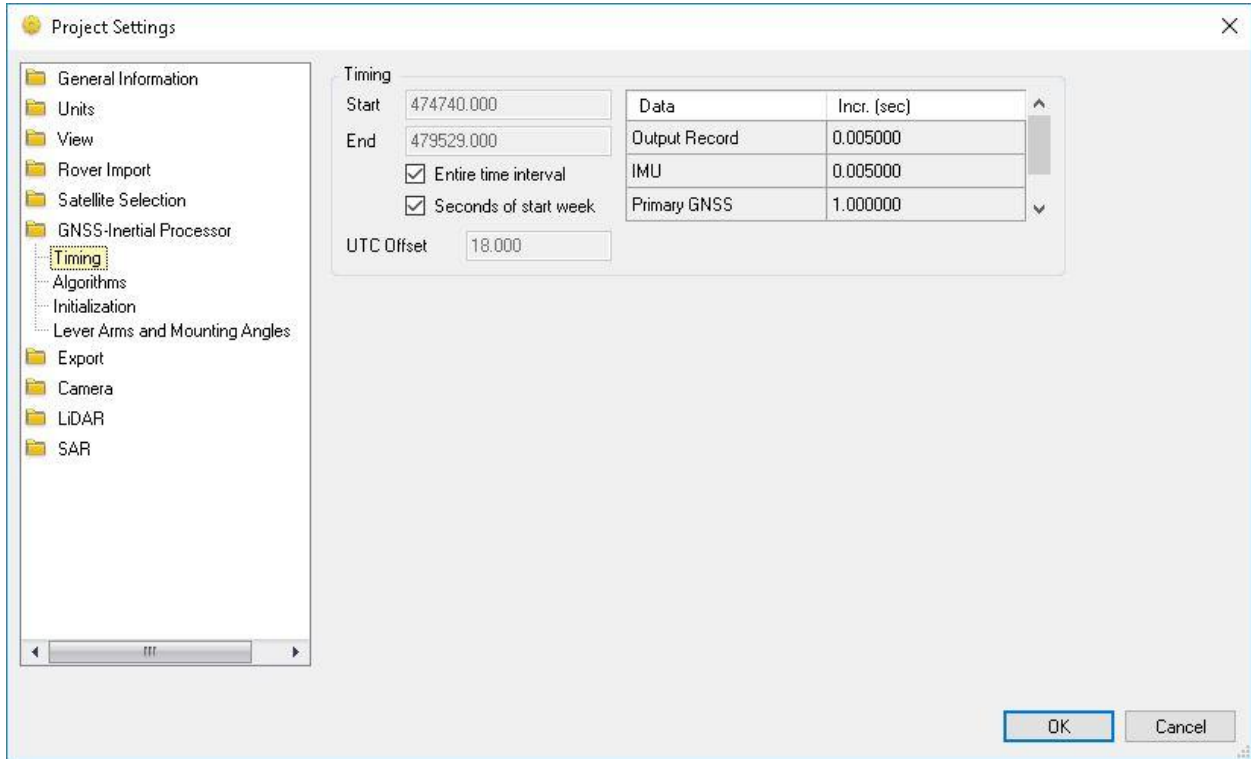
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

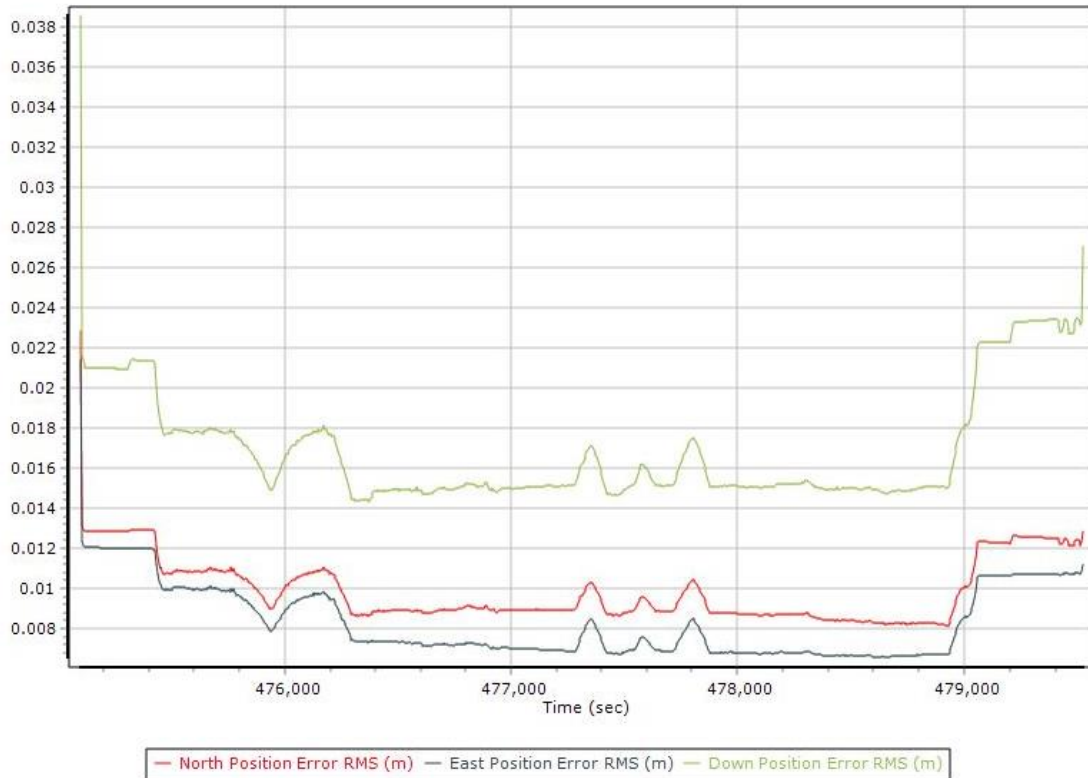
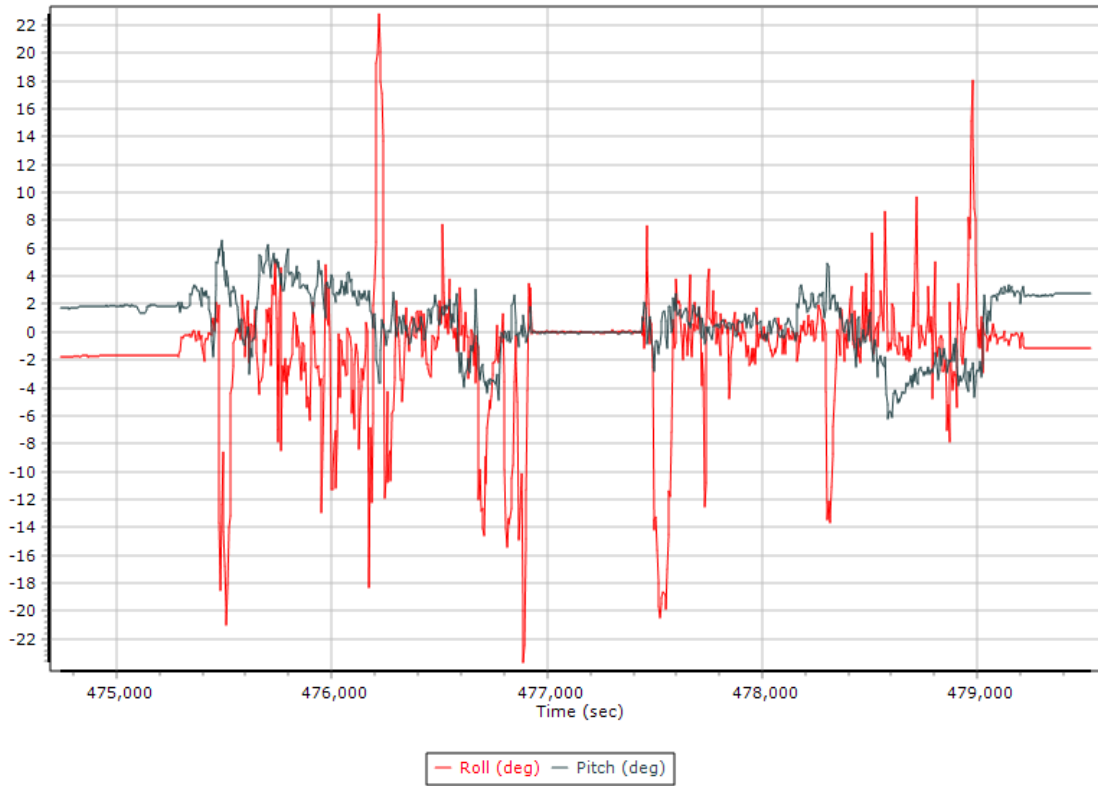
Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.049 m	0.003 m	-1.230 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

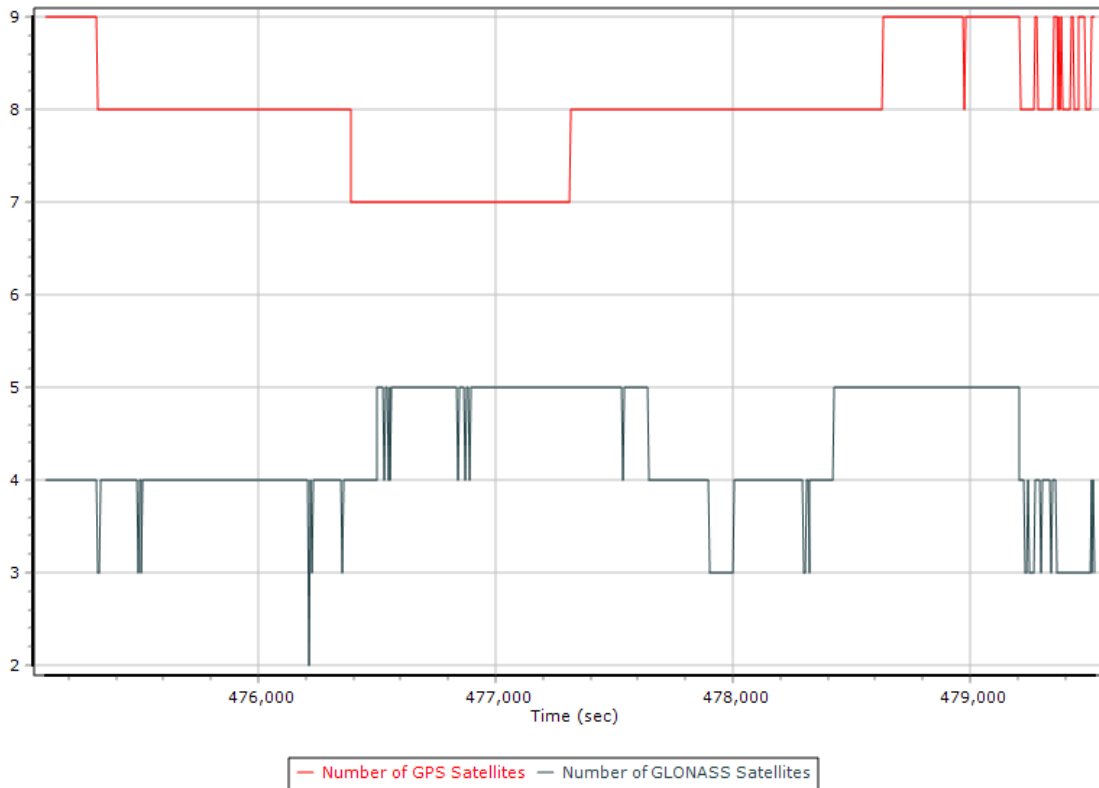
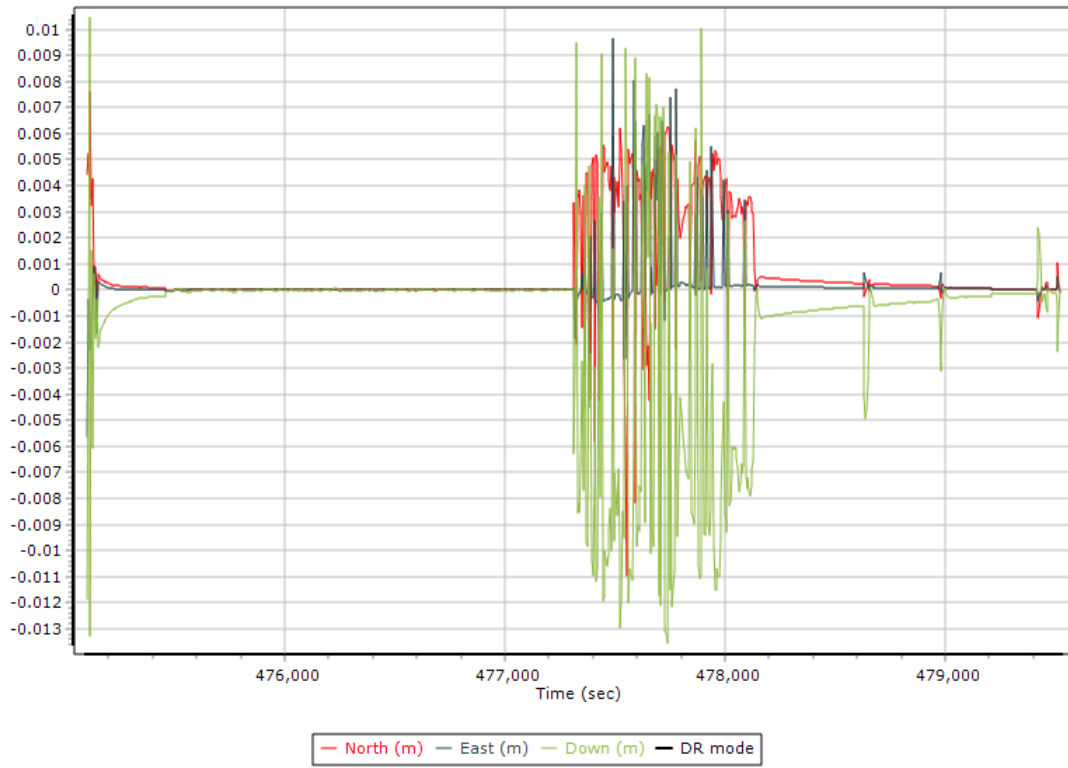
Standard Deviation: <3cm 10cm 50cm 1m 10m

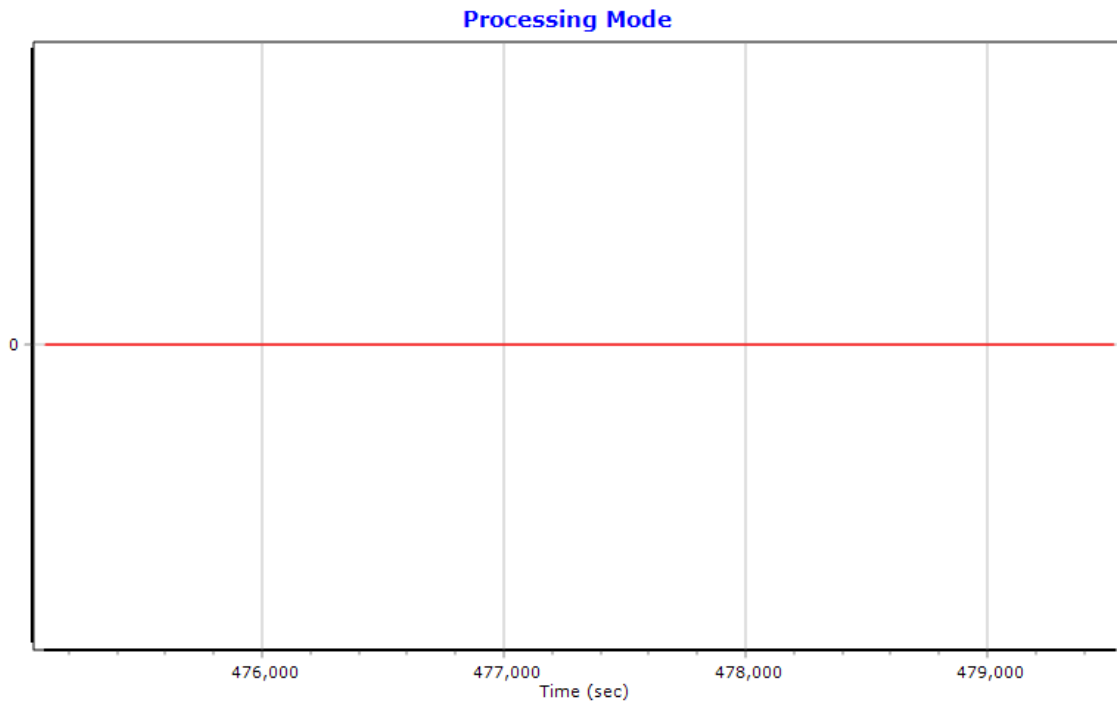
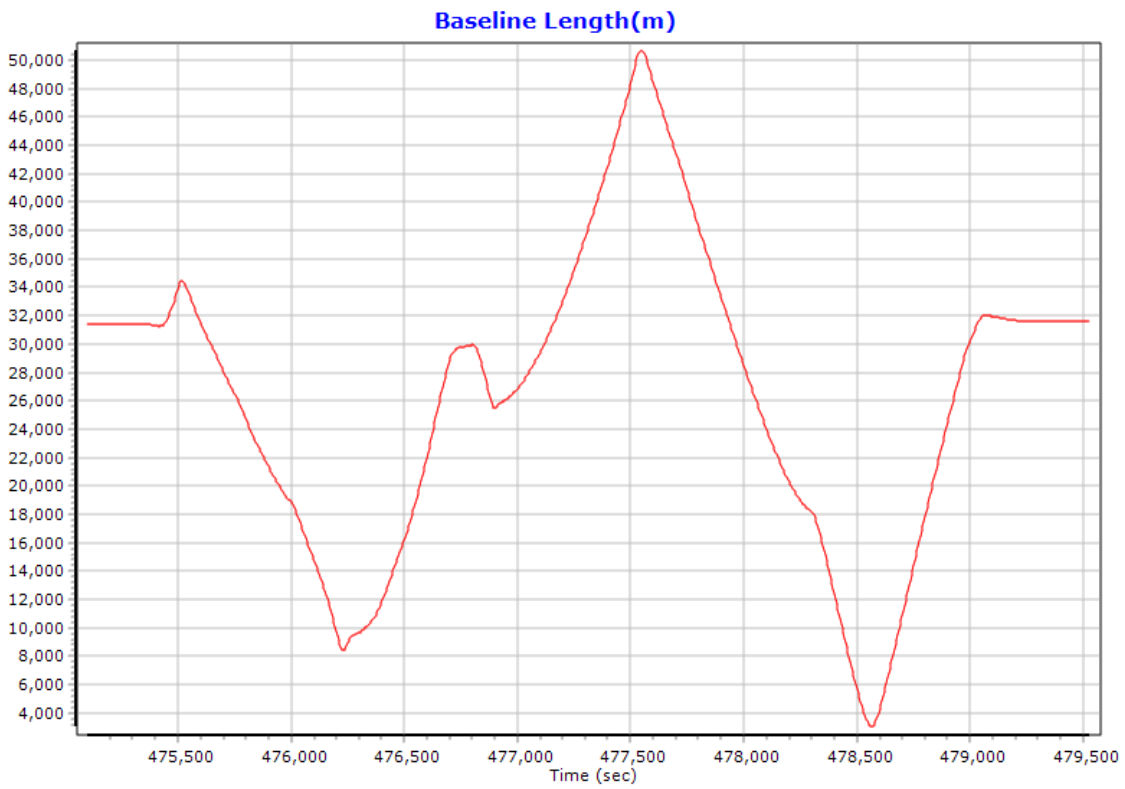
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

OK Cancel





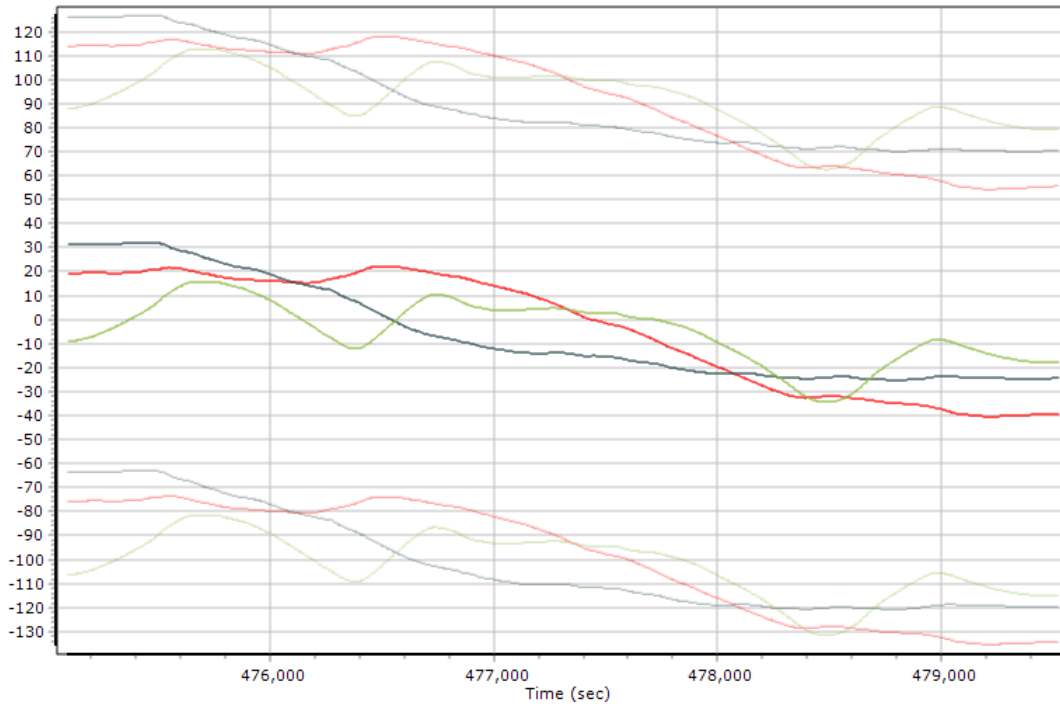




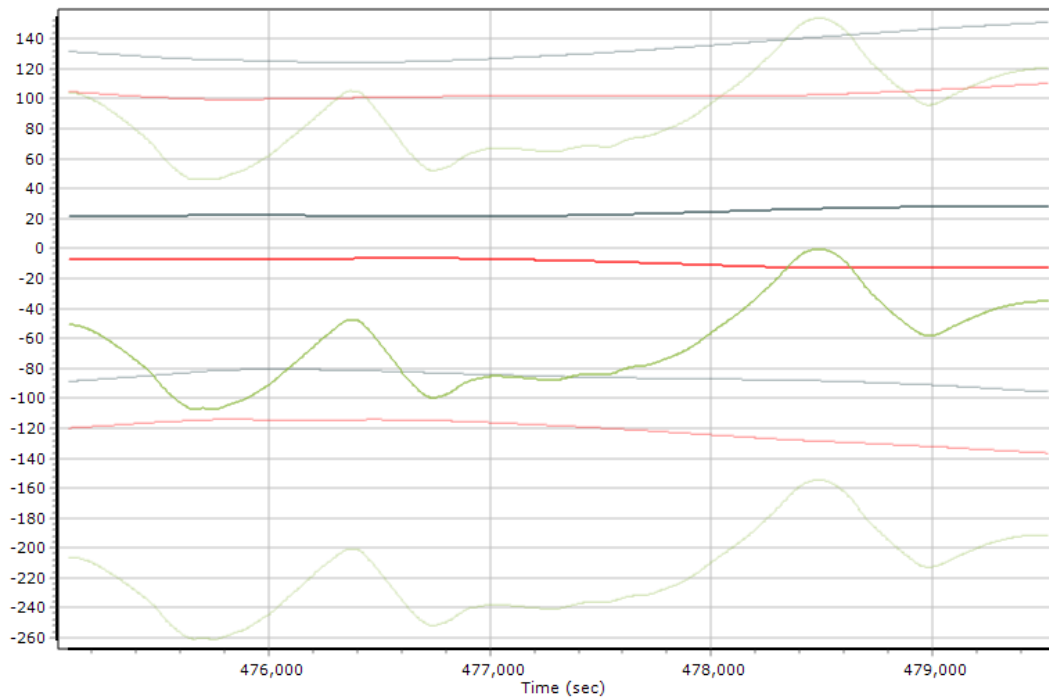
Forward Reverse

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

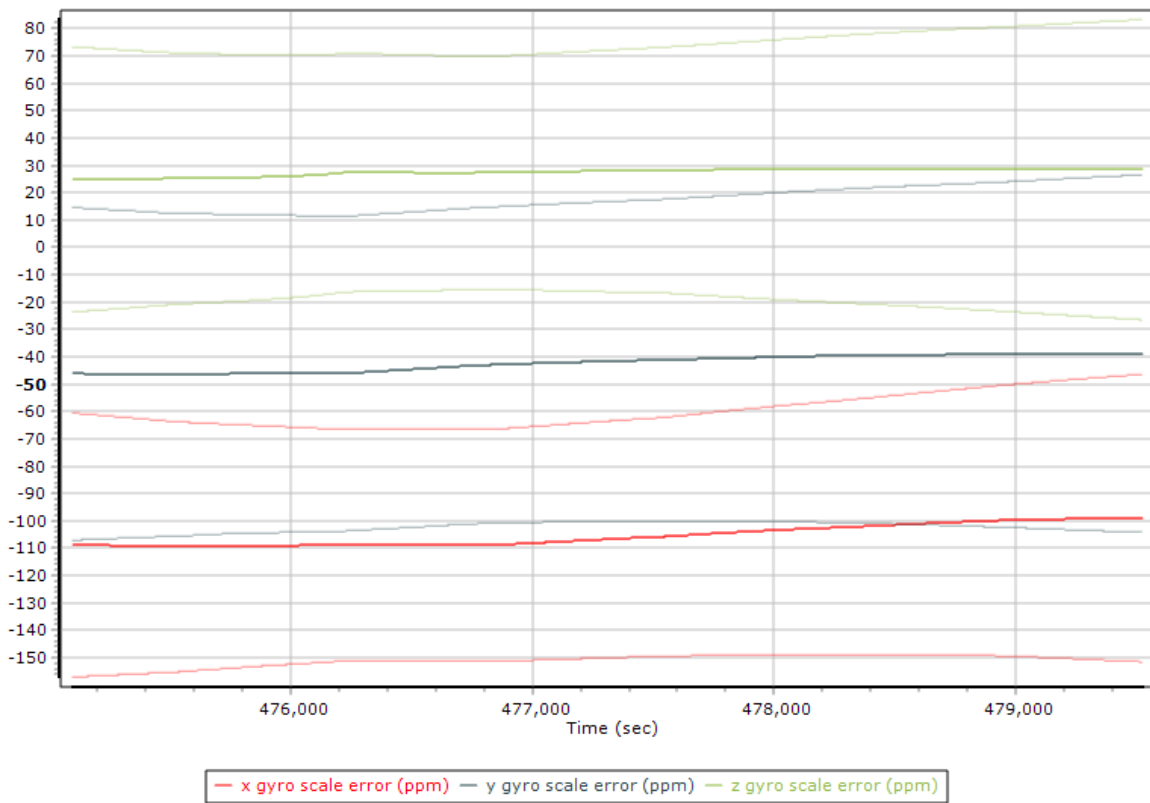
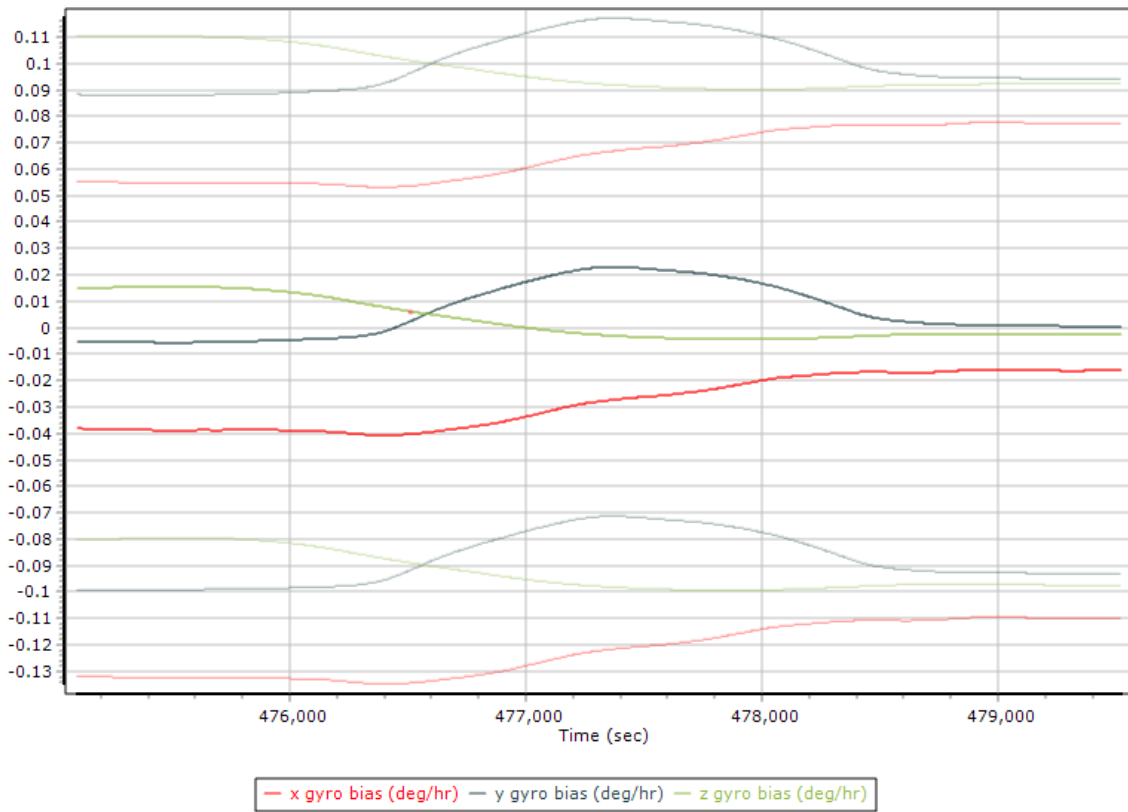
Sensor Errors



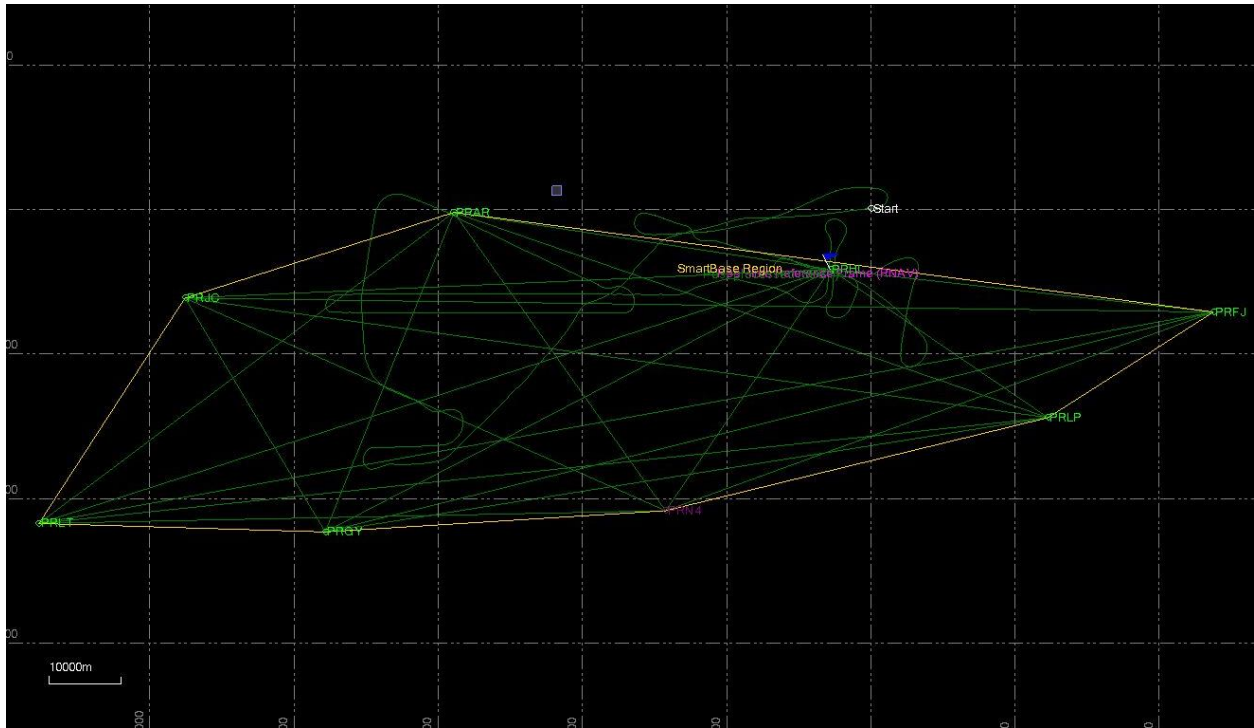
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



45A18315A



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

Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.049 m	0.003 m	-1.230 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	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

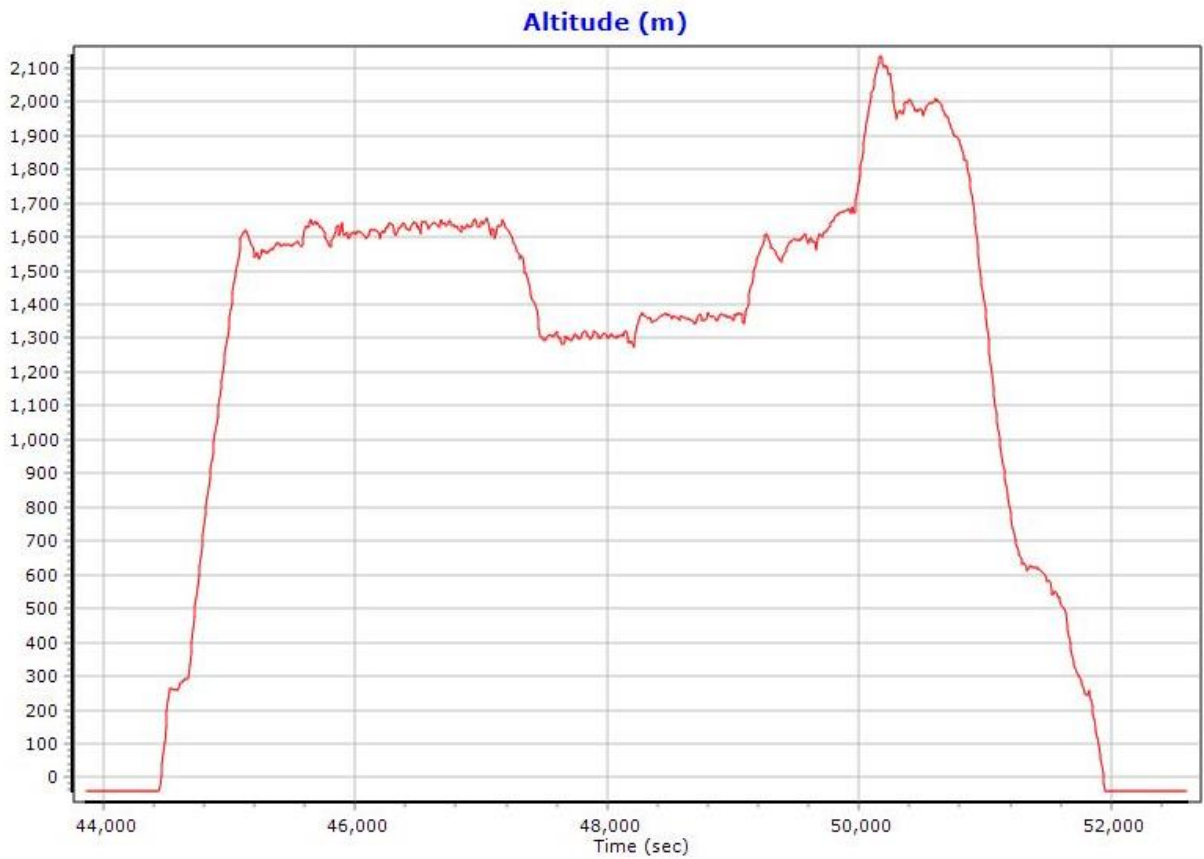
Project Settings

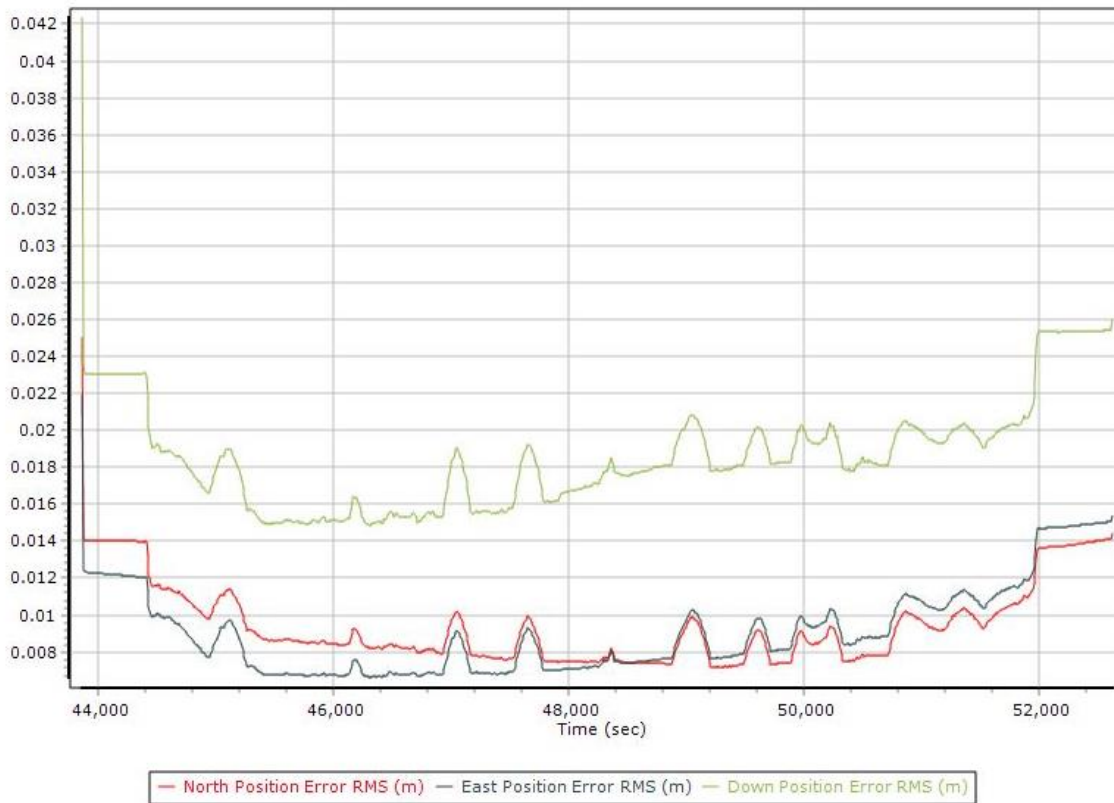
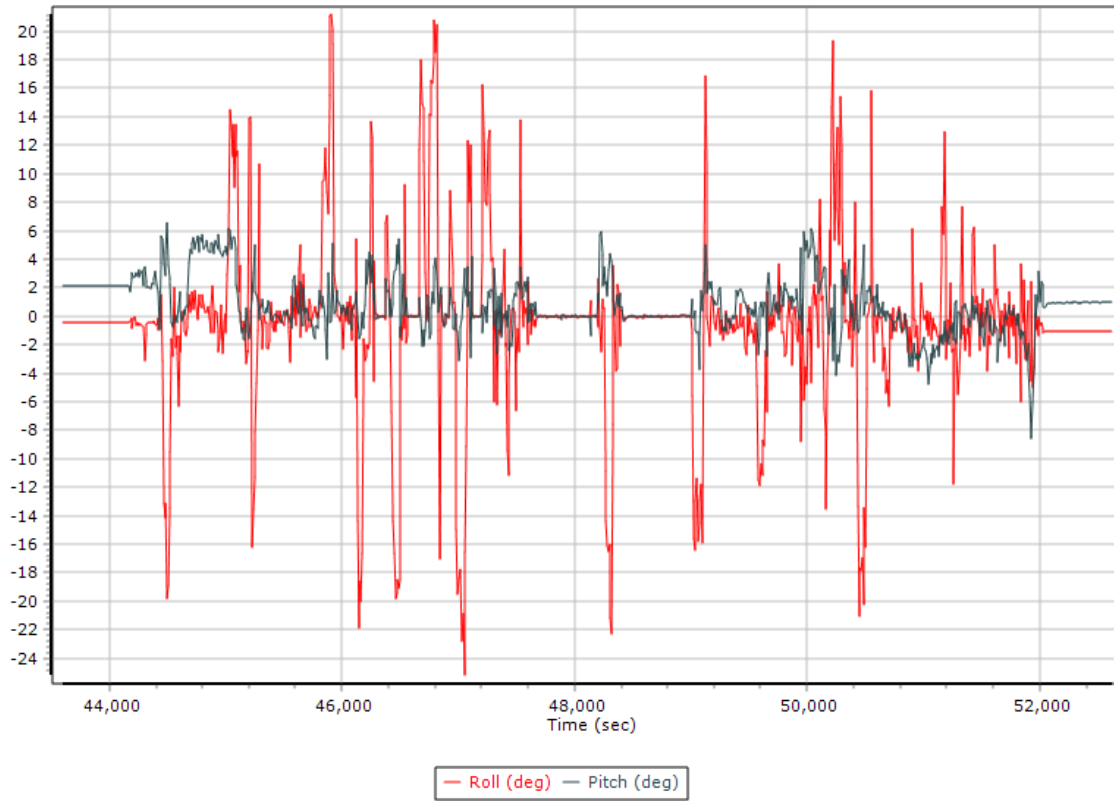
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
 Timing
 Algorithms
 Initialization
 Lever Arms and Mounting Angles
Export
Camera
LIDAR
SAR

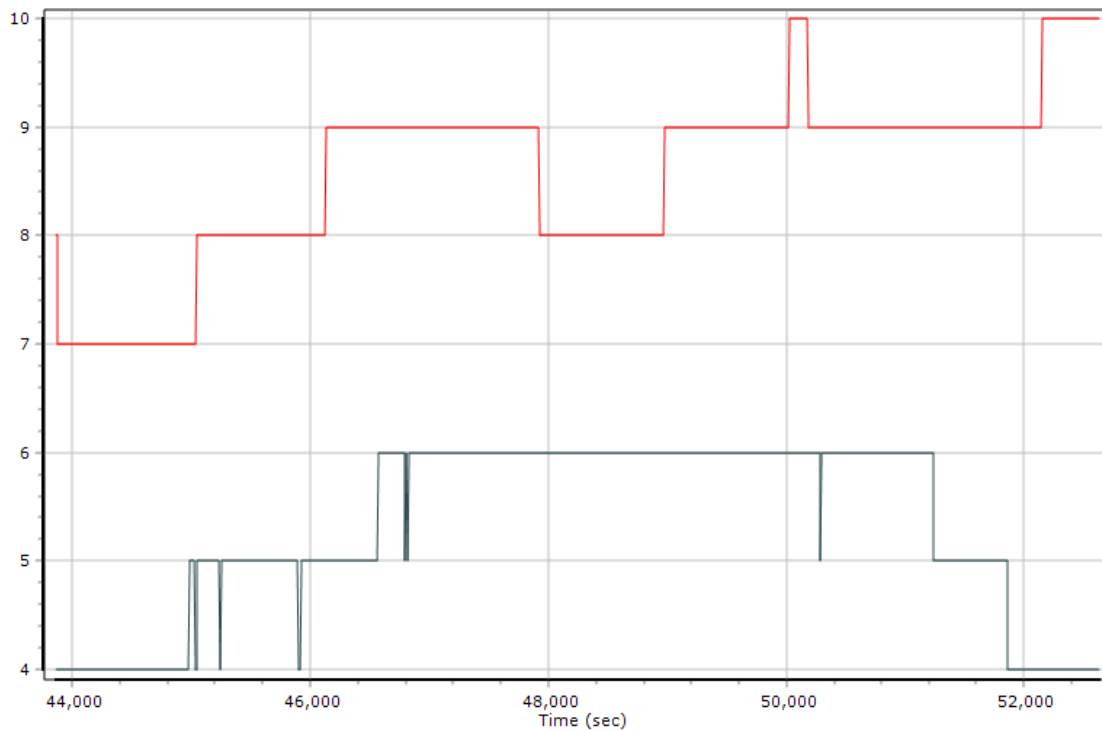
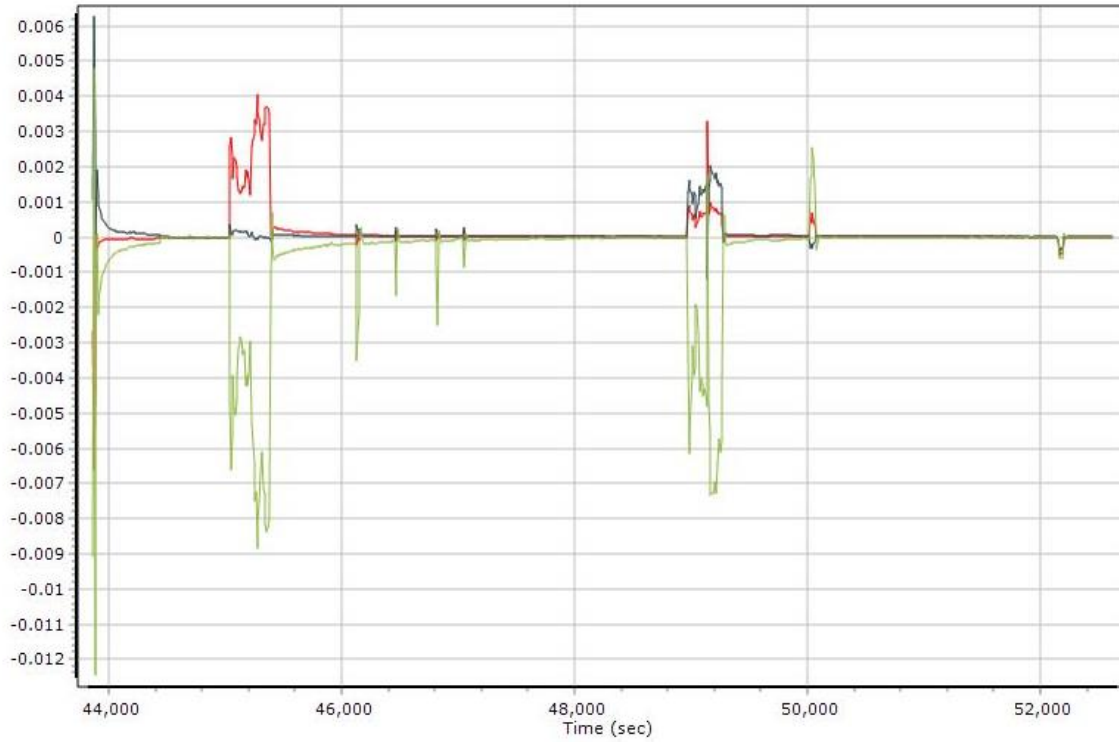
Timing
Start: 43599.000
End: 52630.000
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

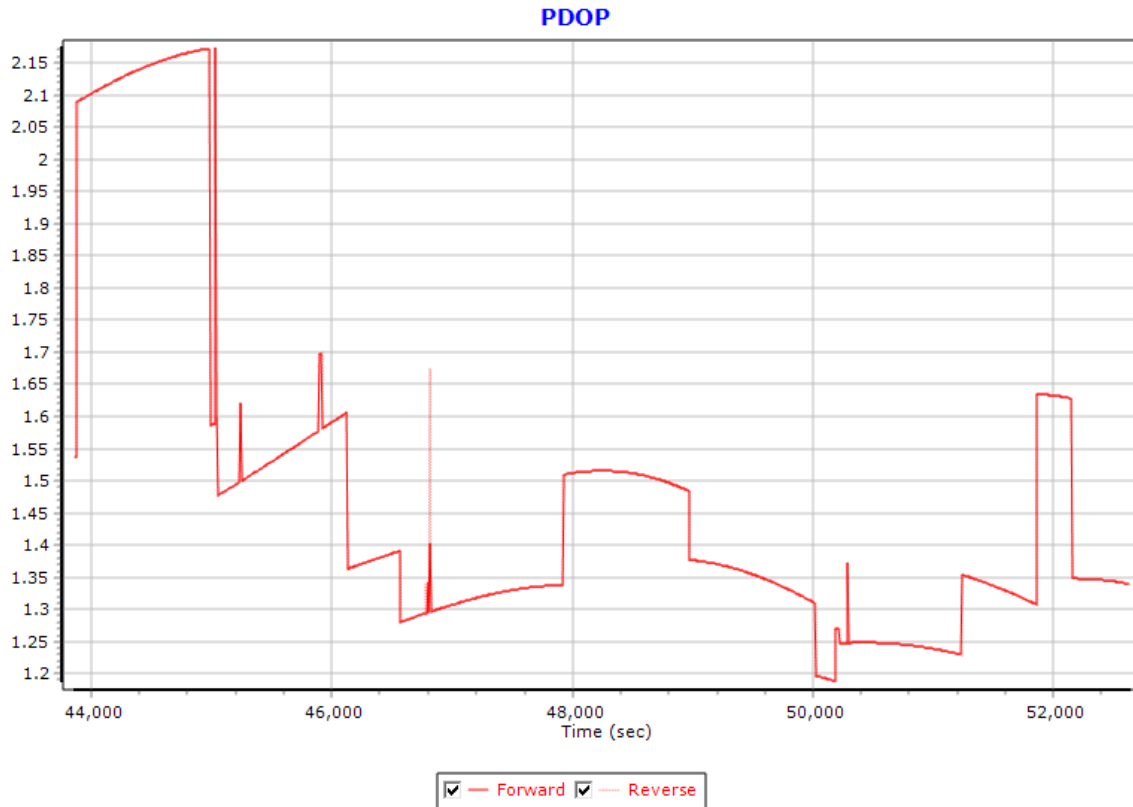
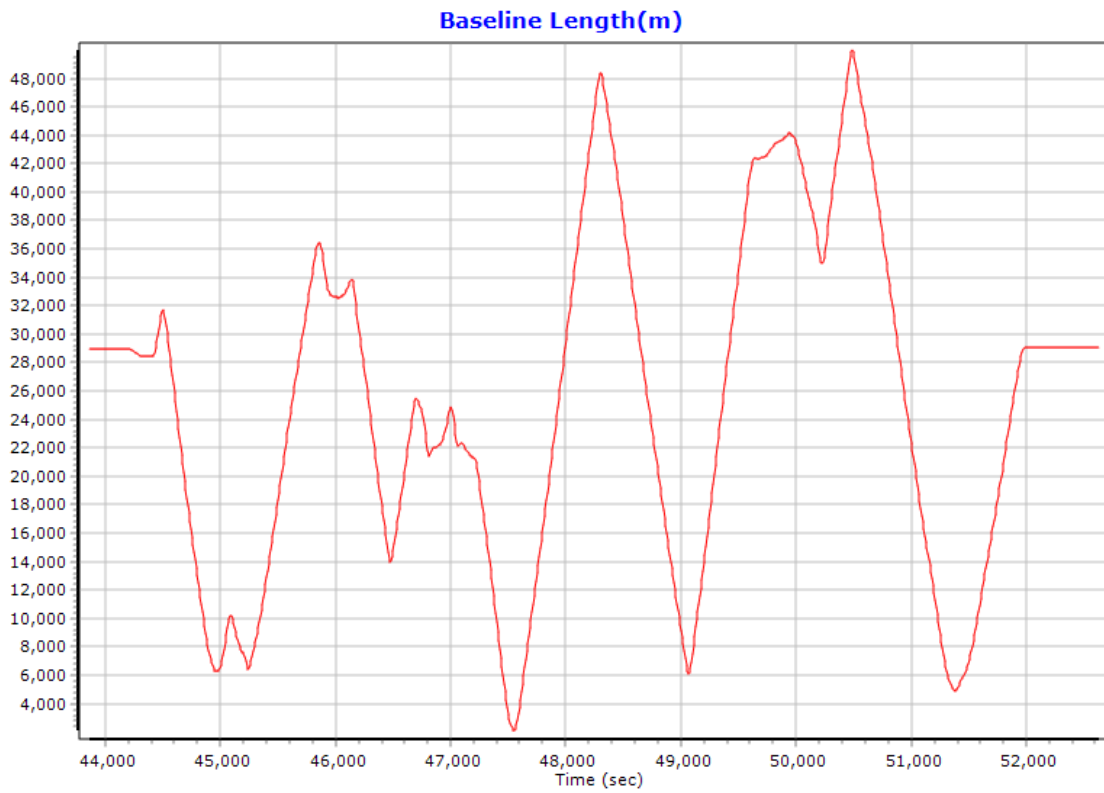
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel

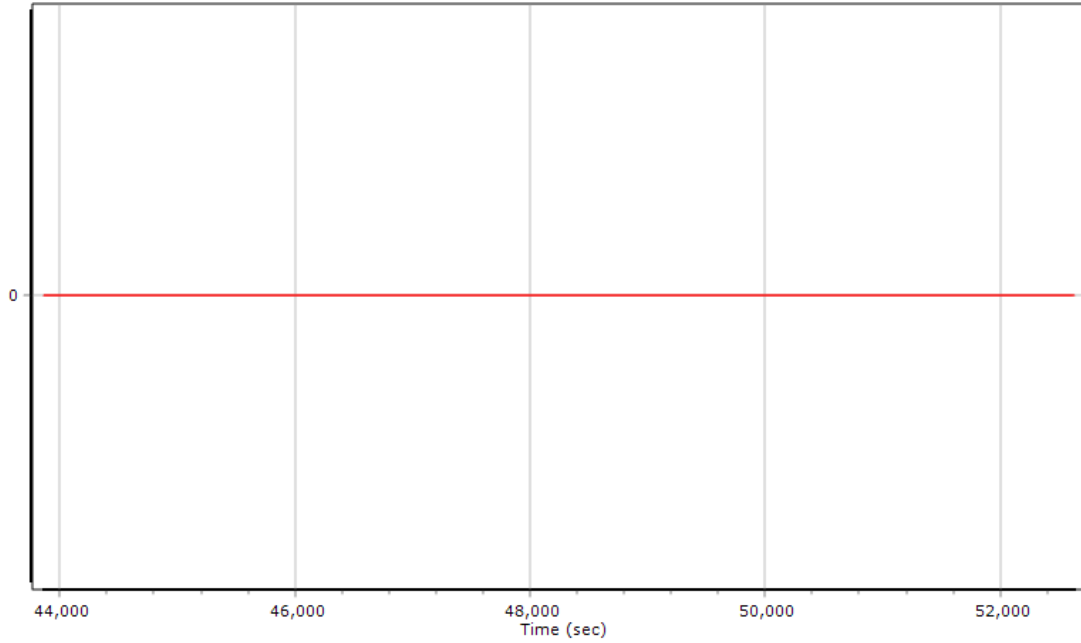








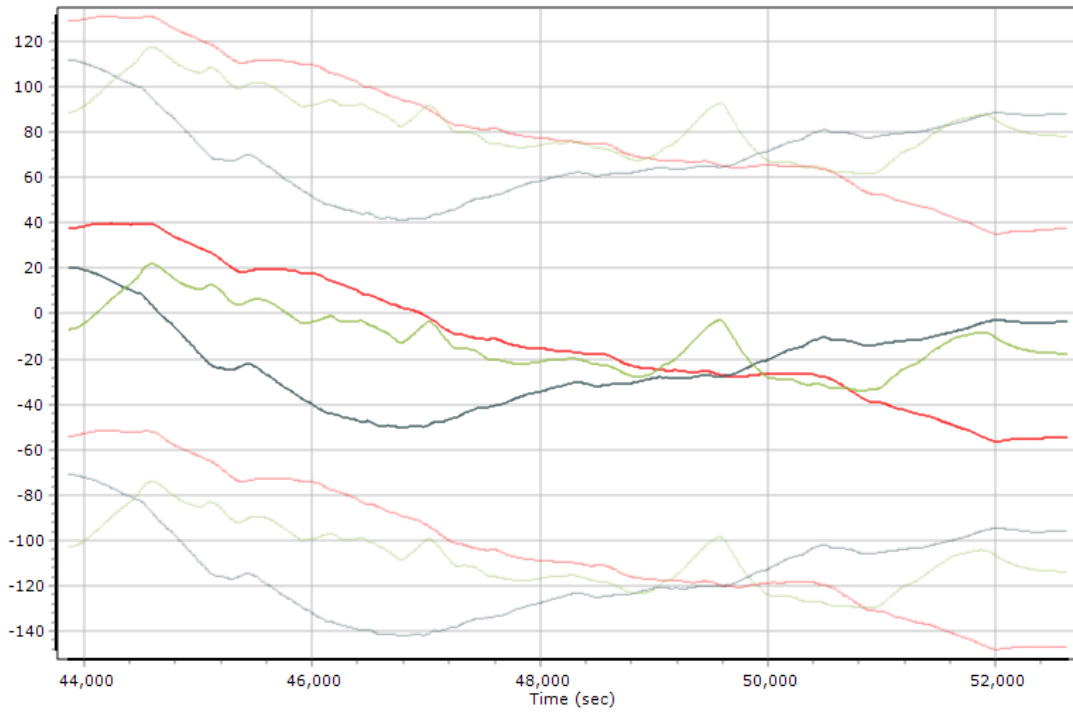
Processing Mode



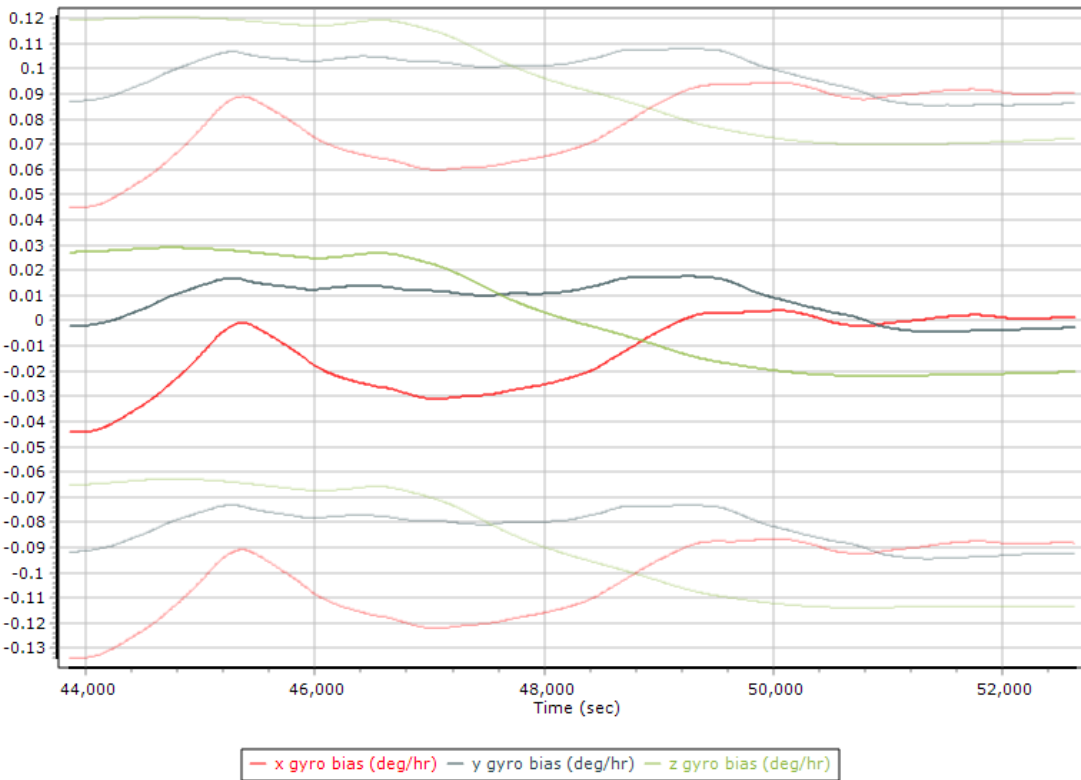
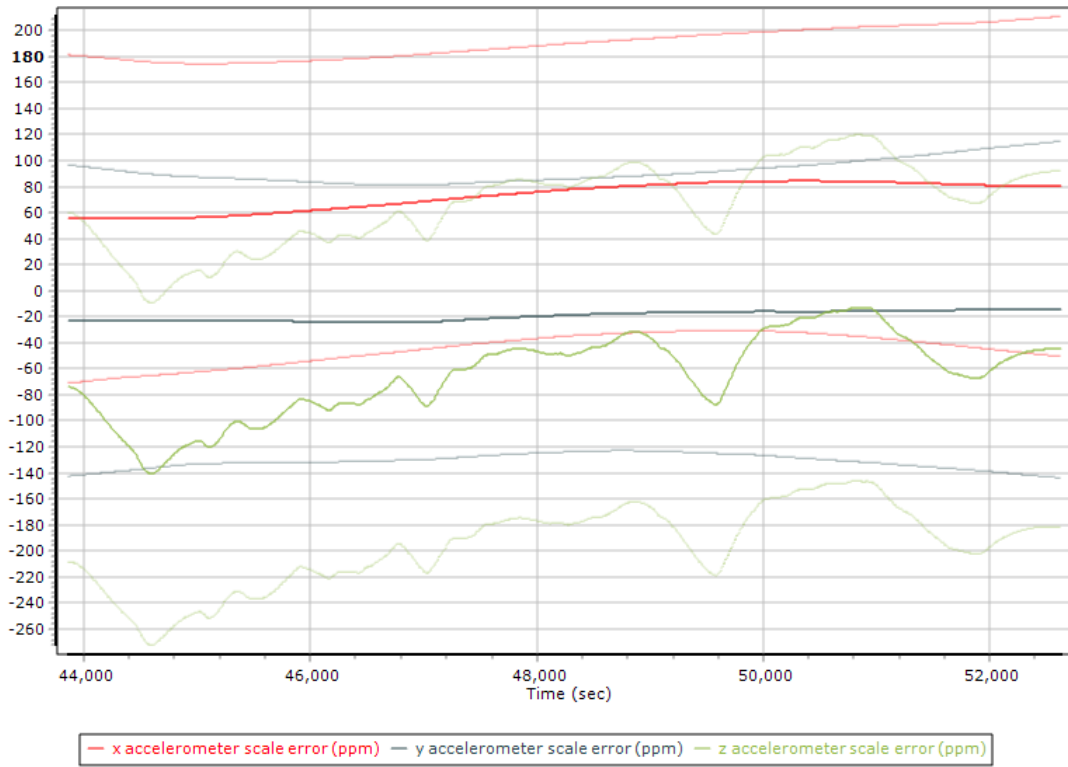
Forward Reverse

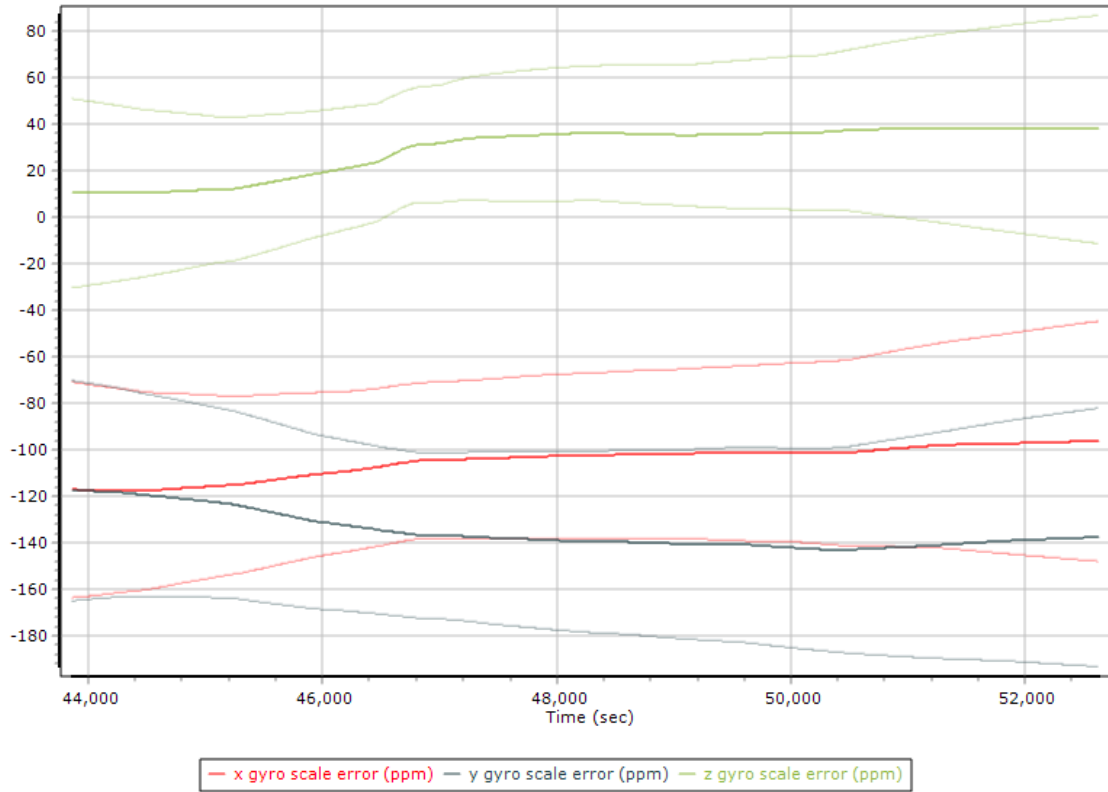
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

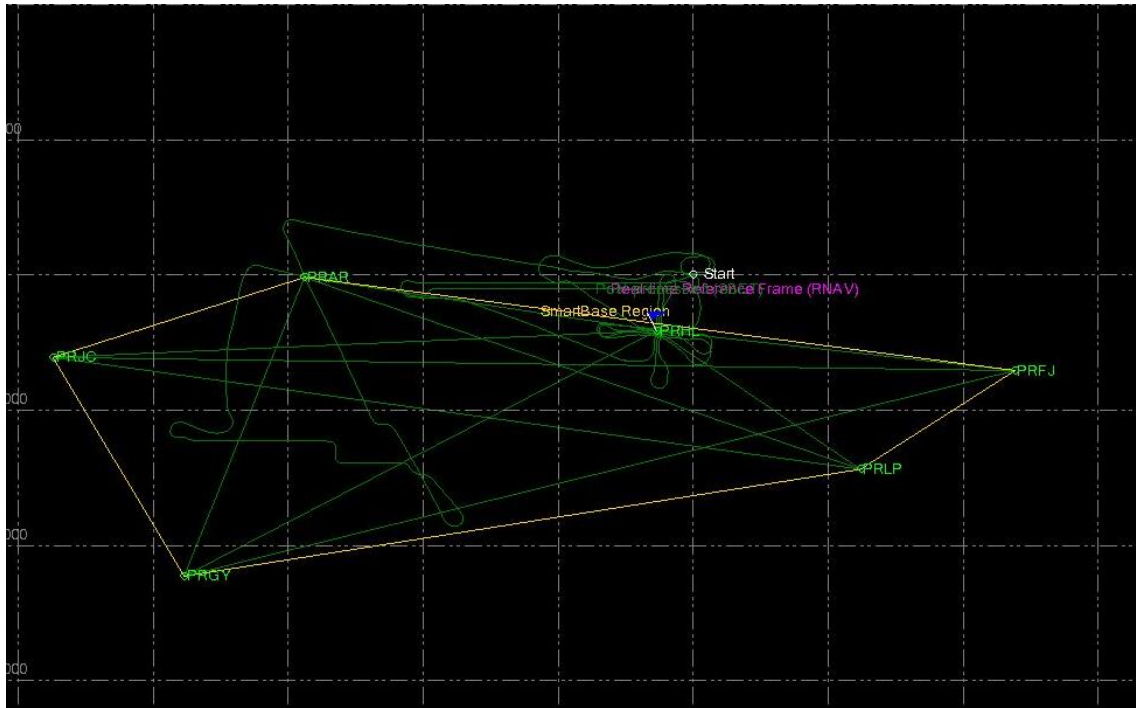


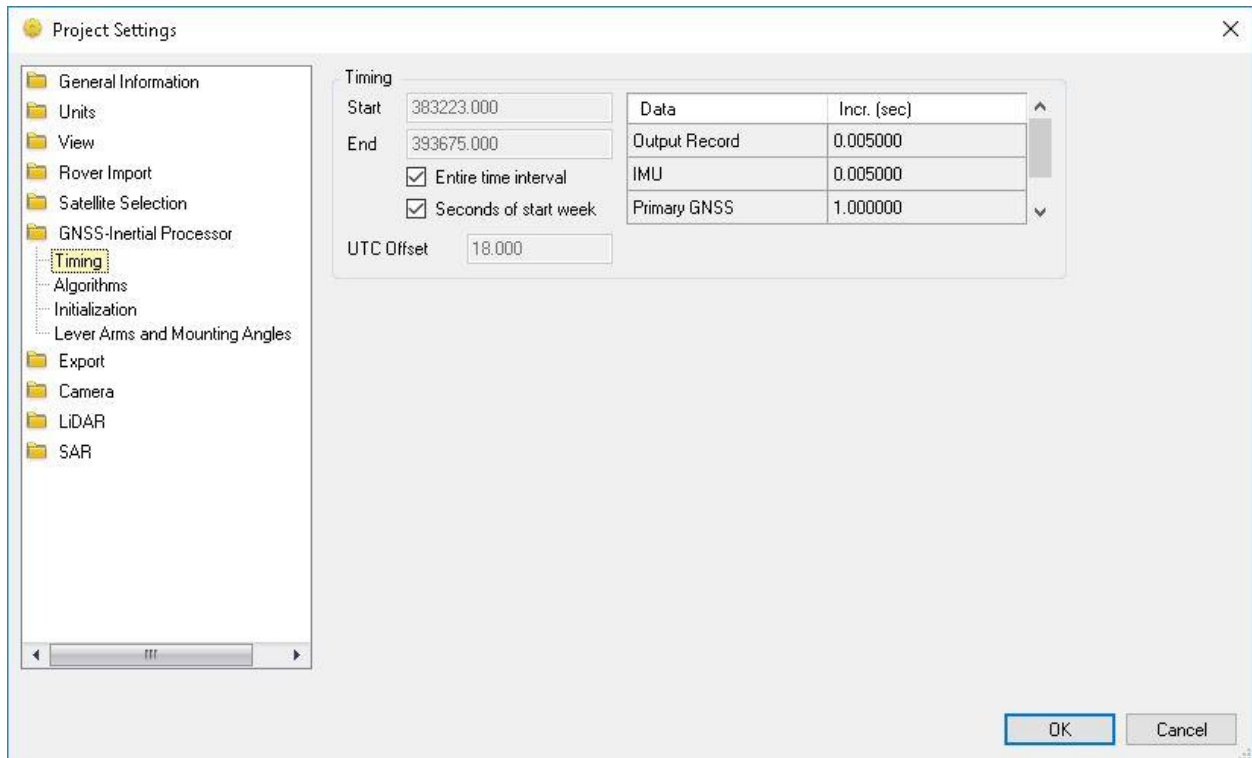
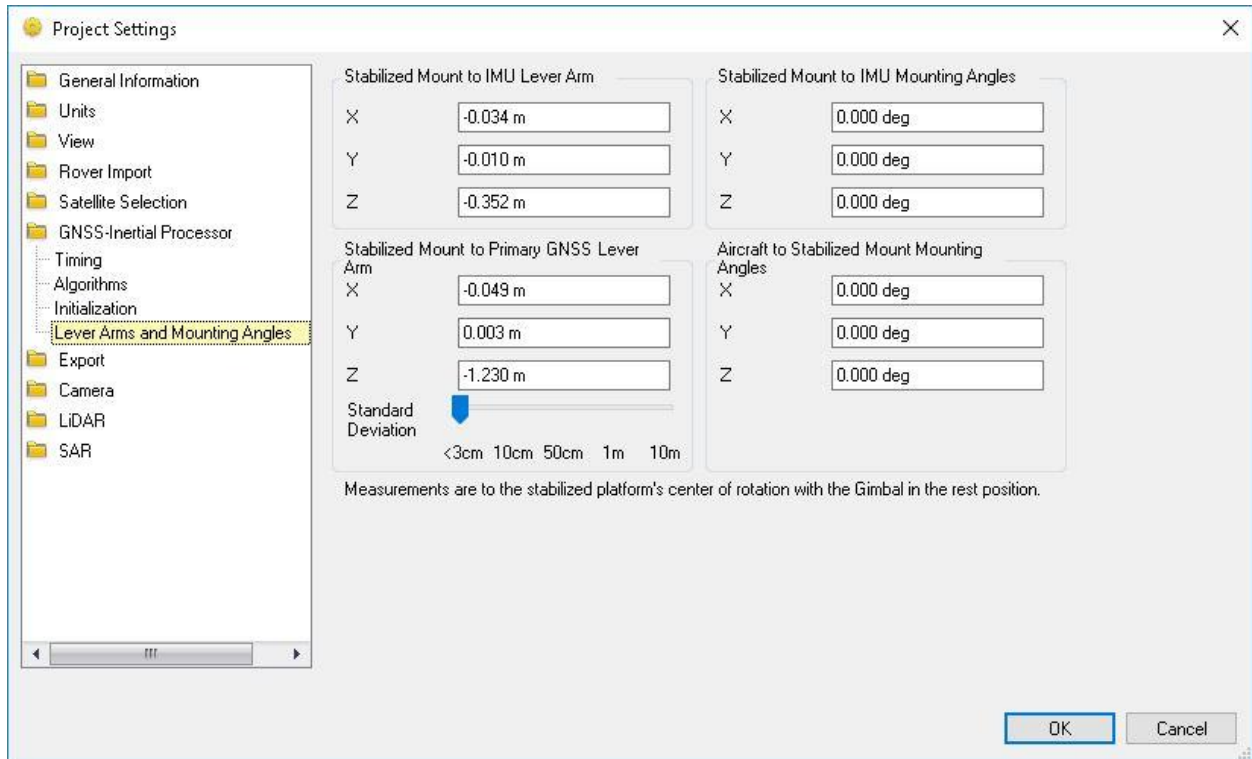
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)

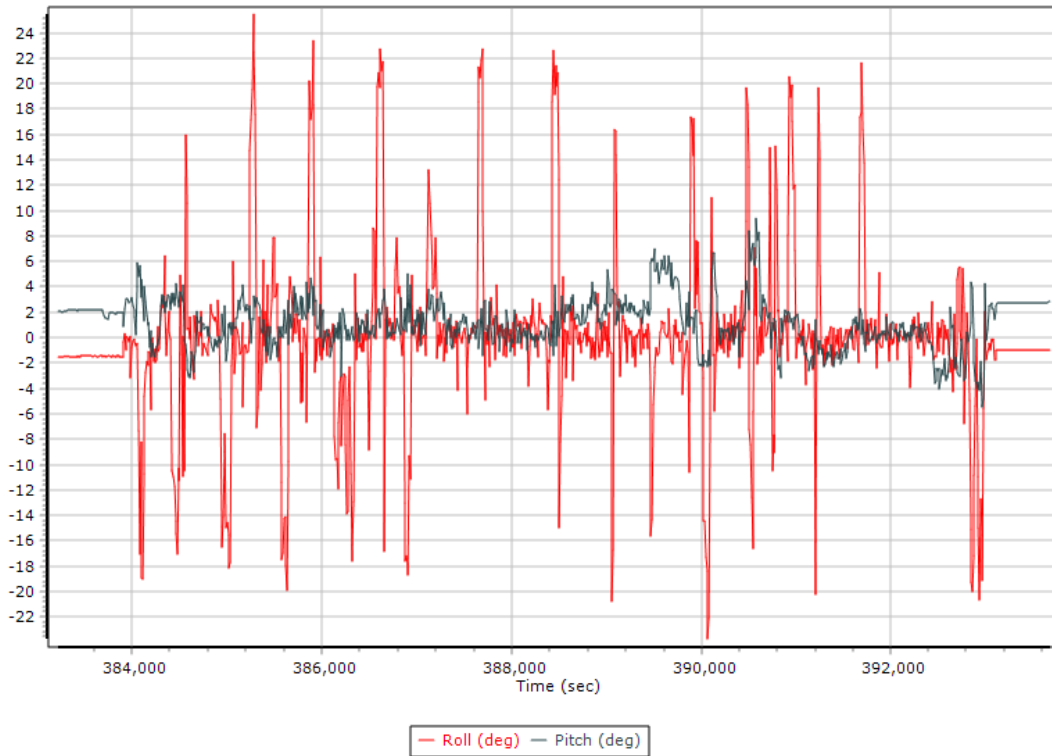
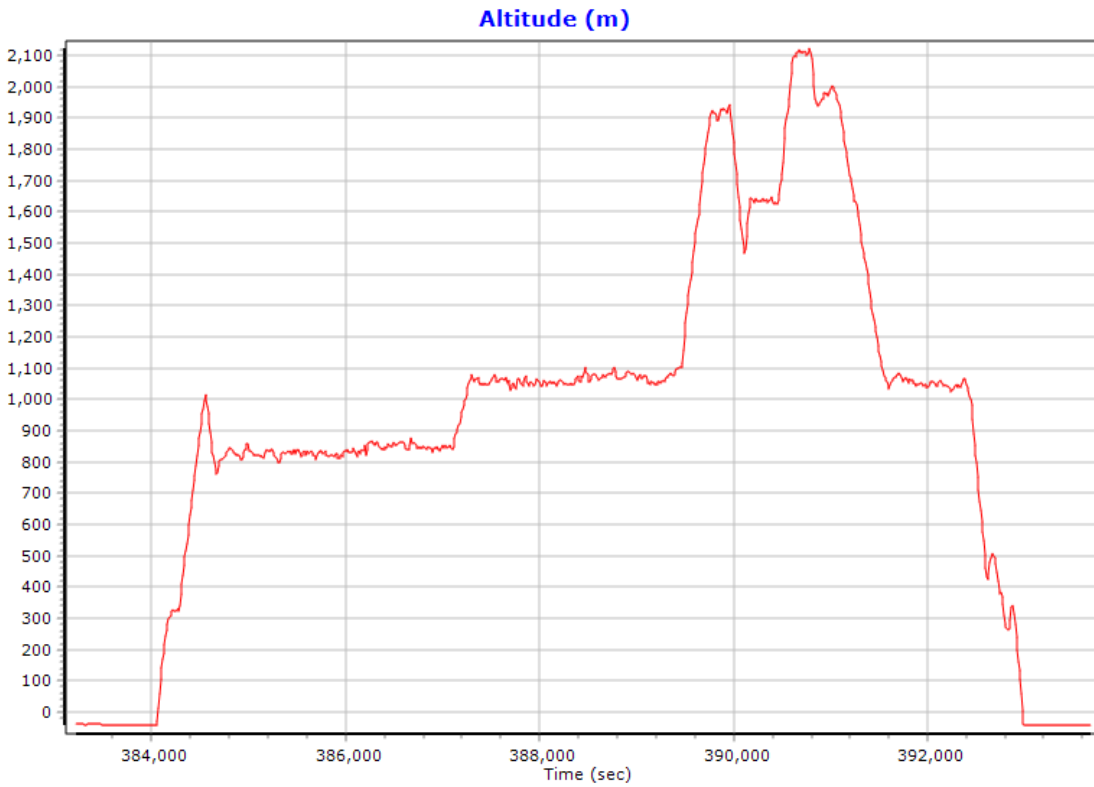


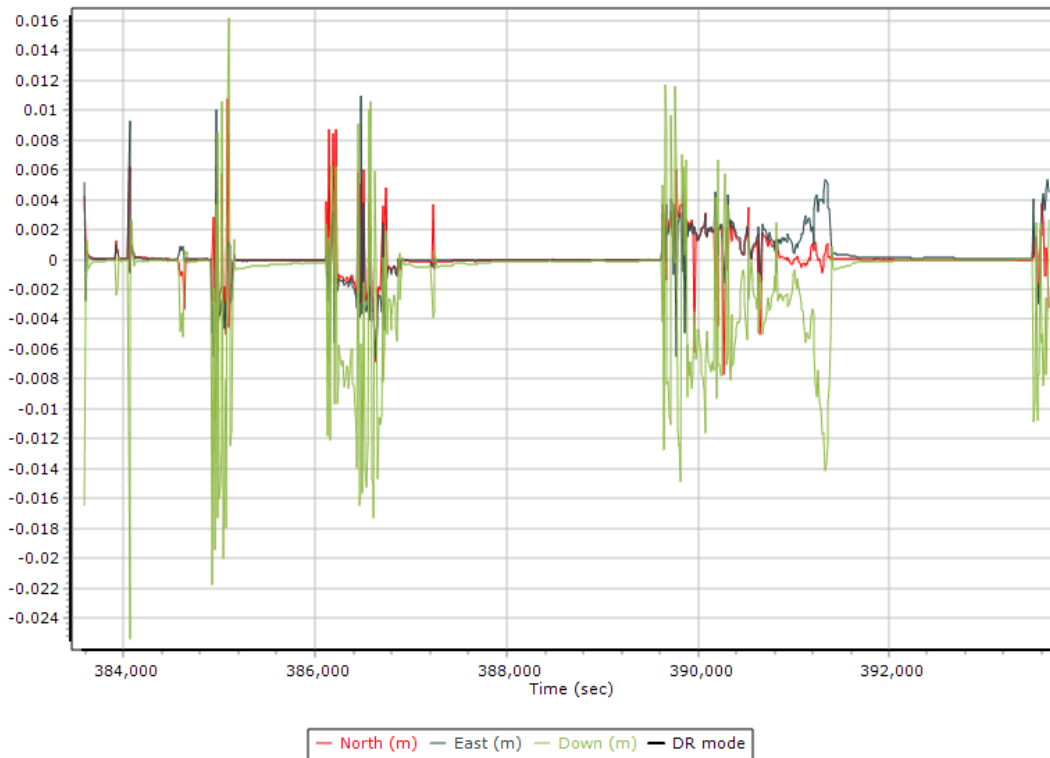
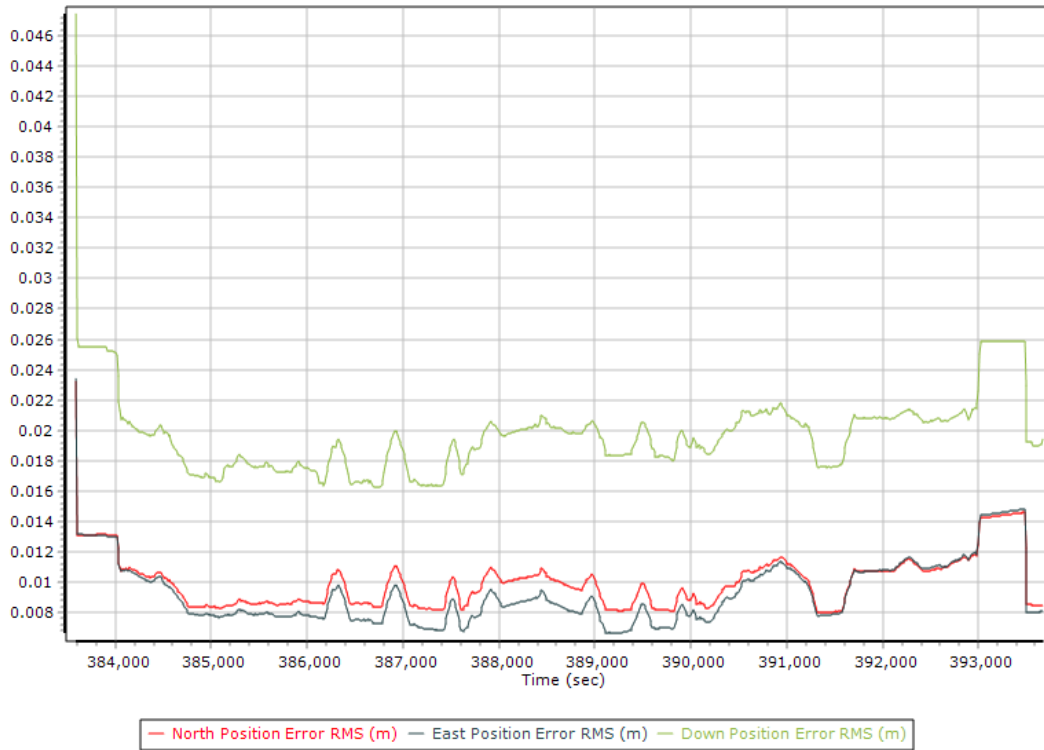


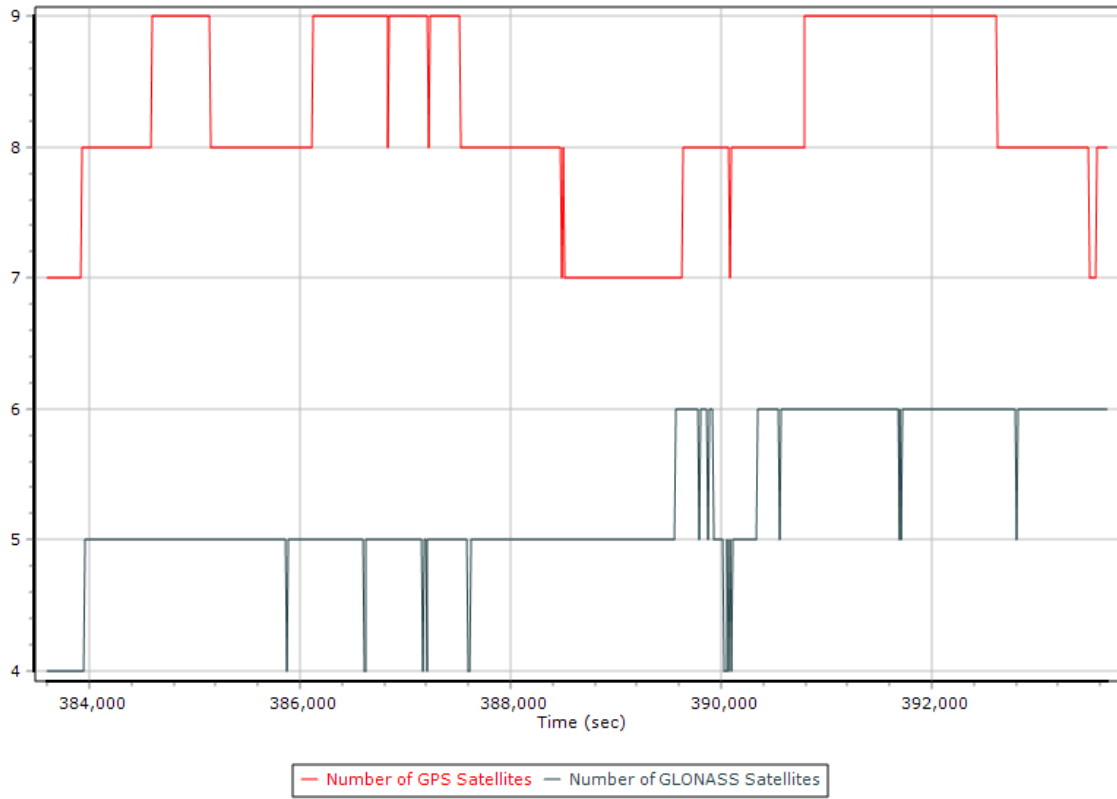
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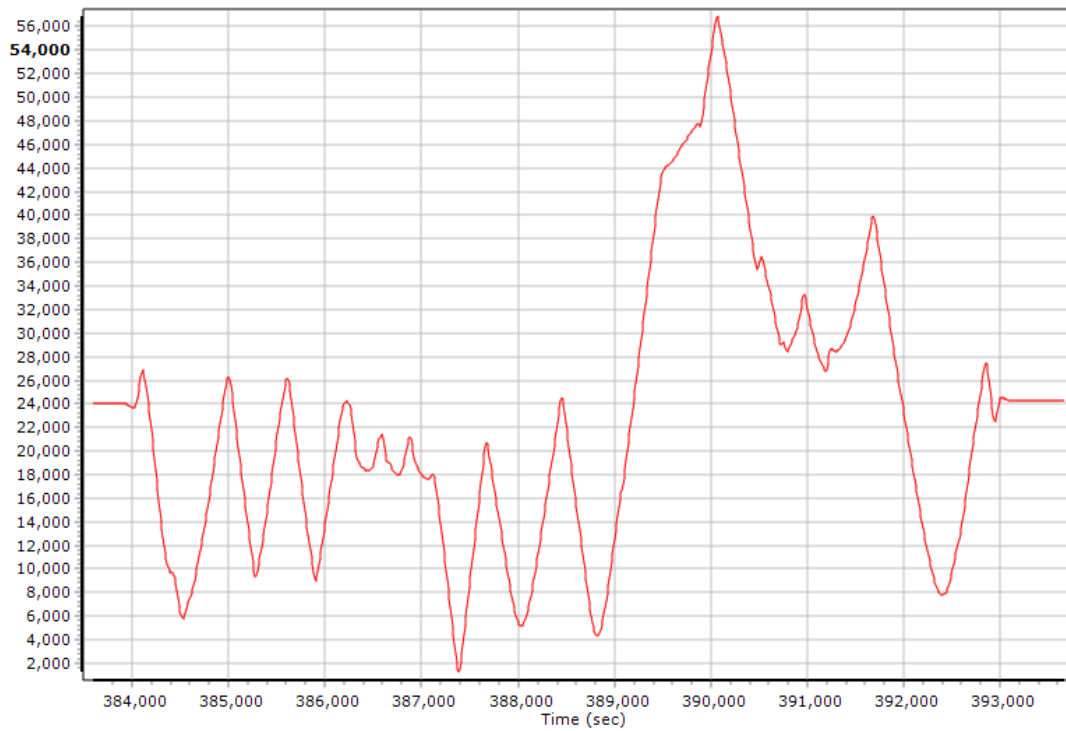




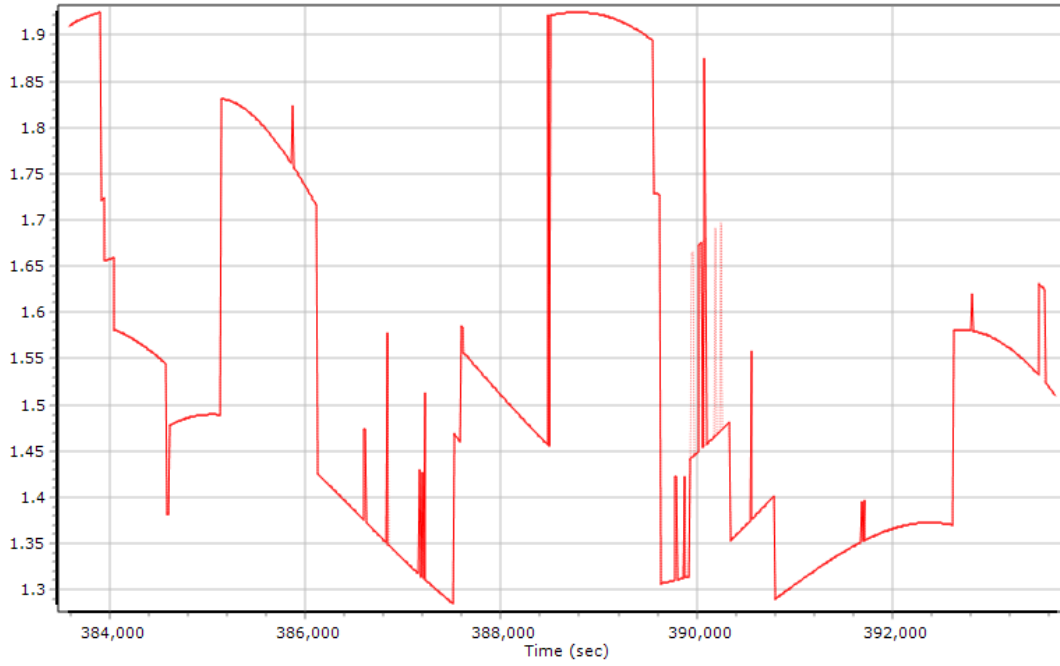




Baseline Length(m)

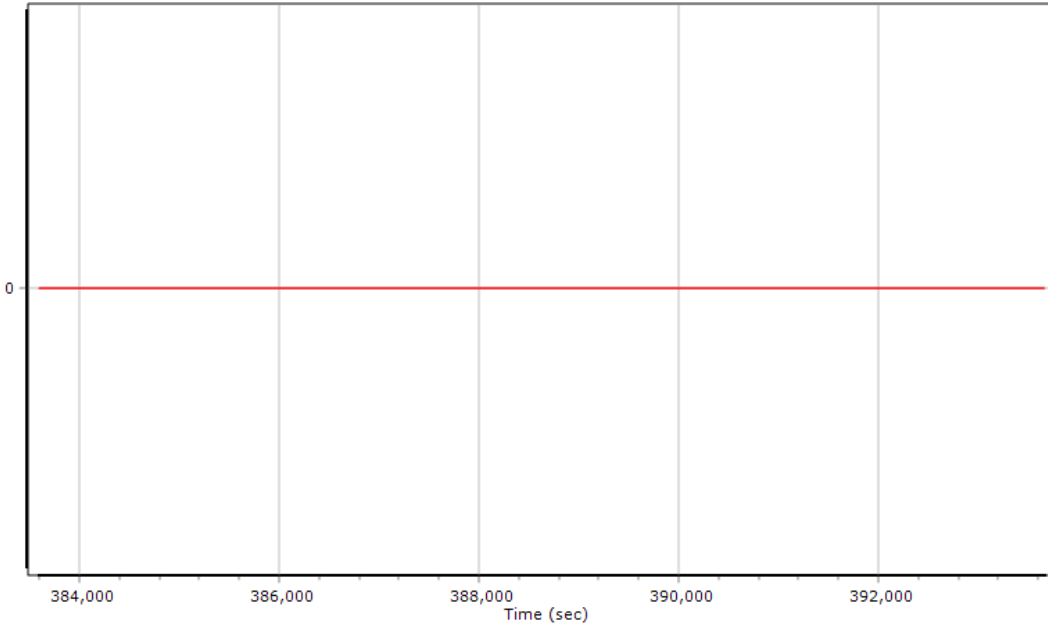


PDOP



Forward Reverse

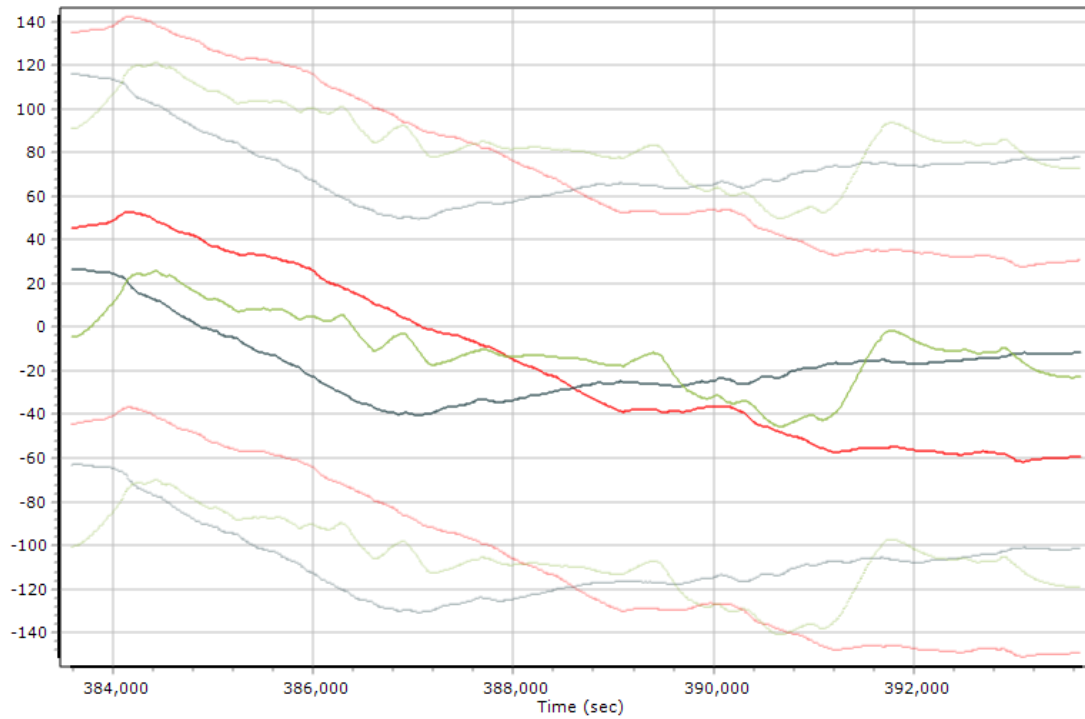
Processing Mode



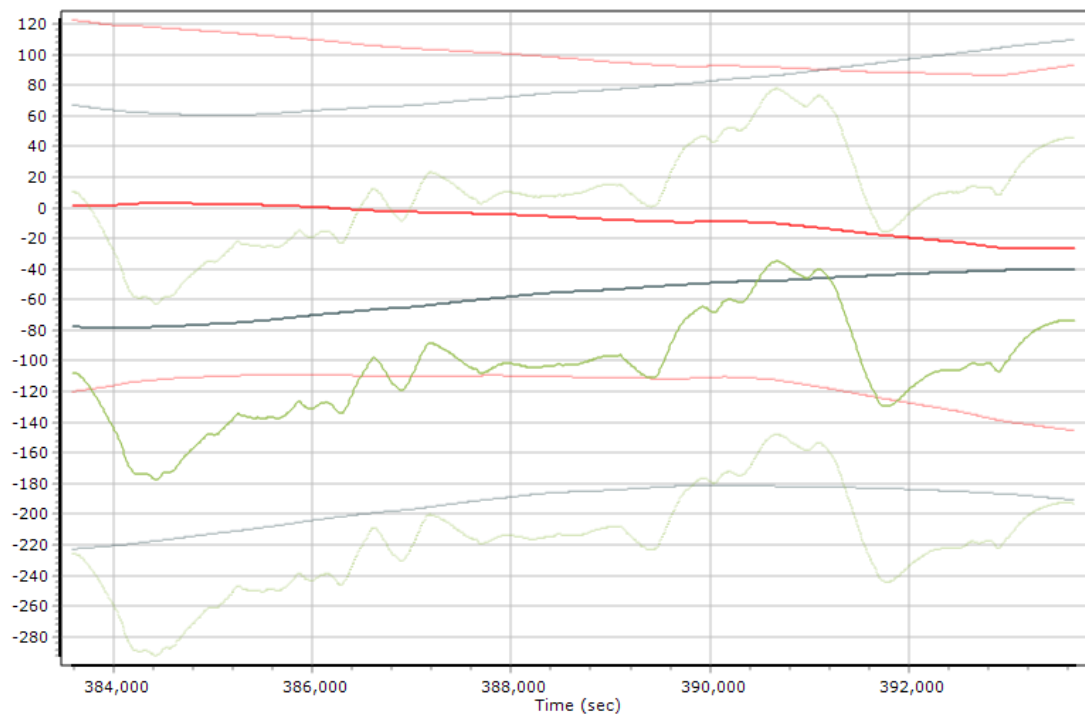
Forward Reverse

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

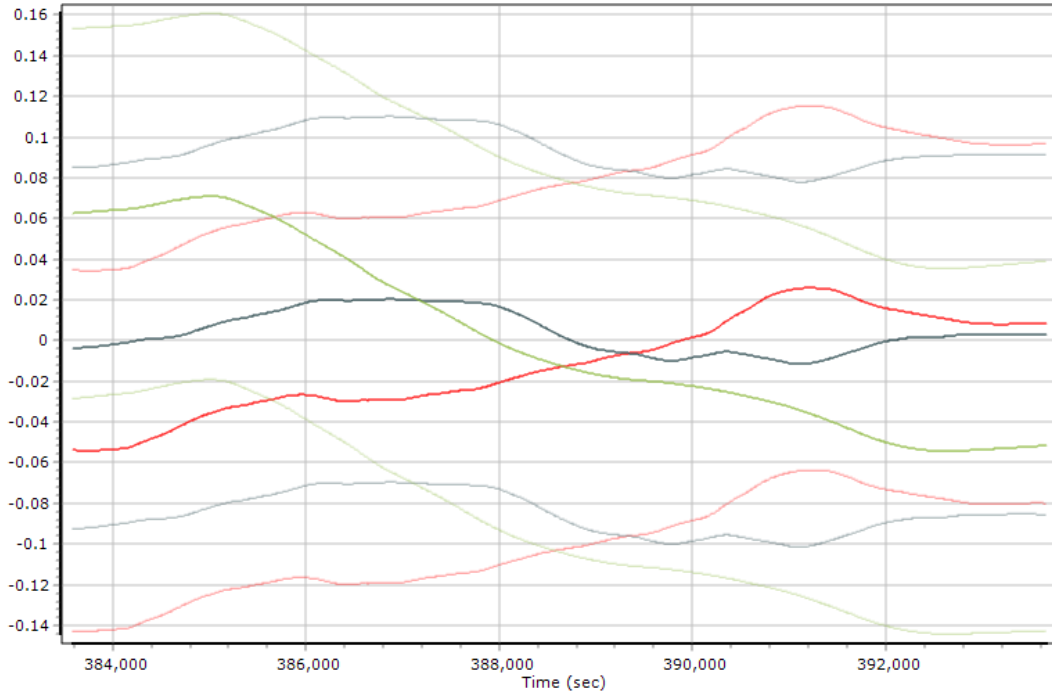
Sensor Errors



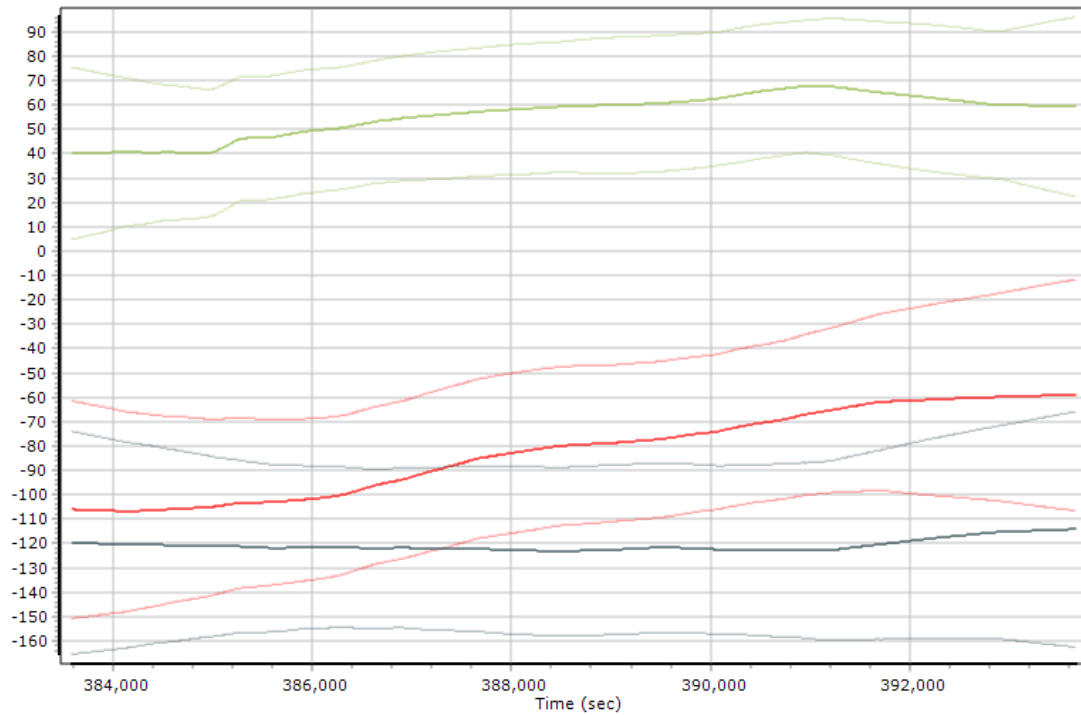
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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

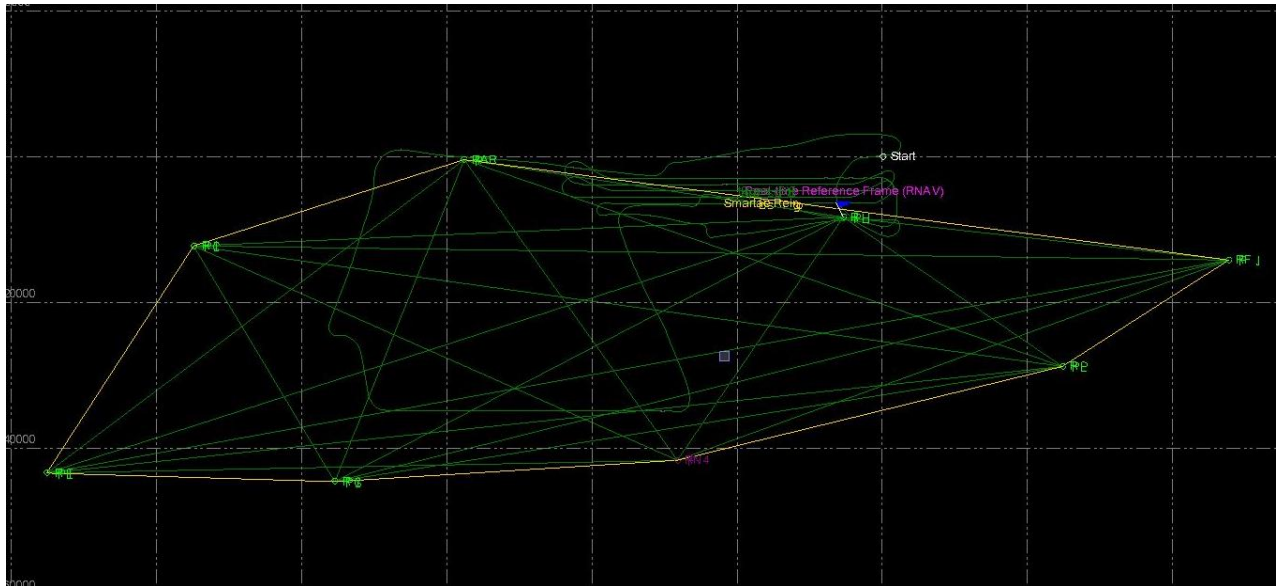


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



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

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Project Settings

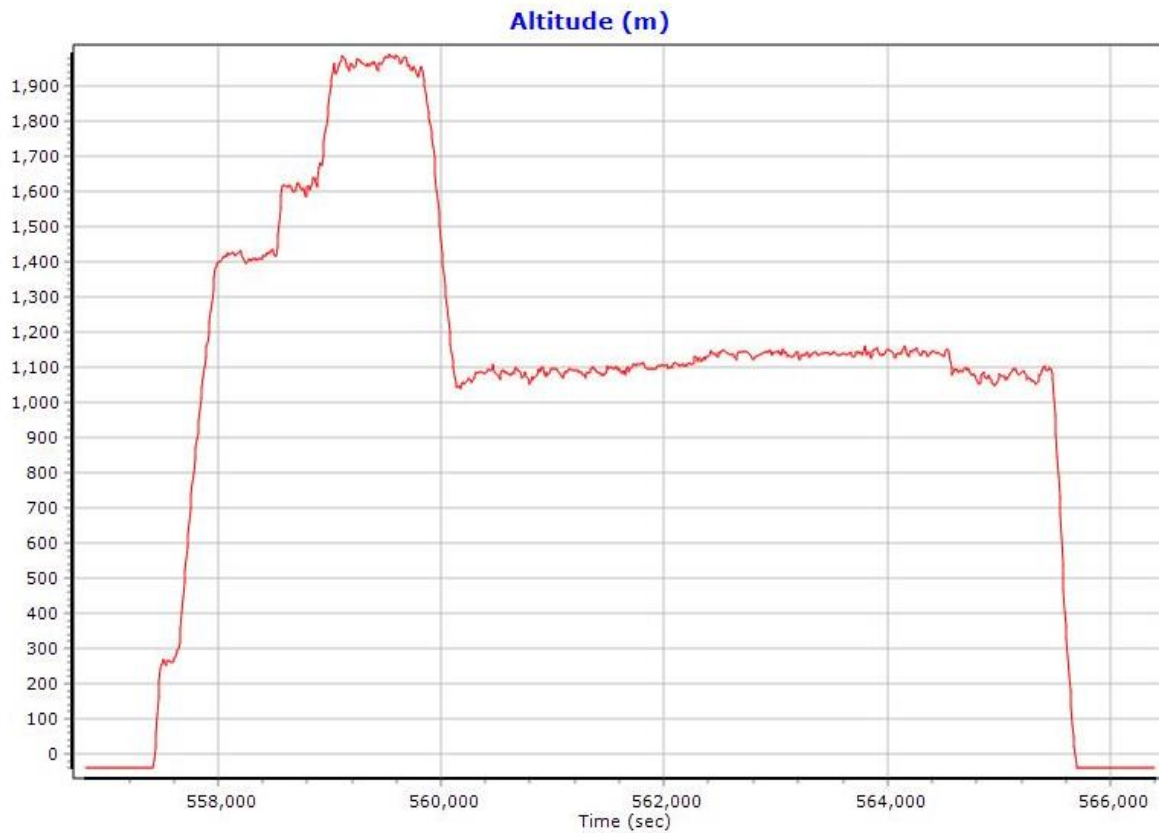
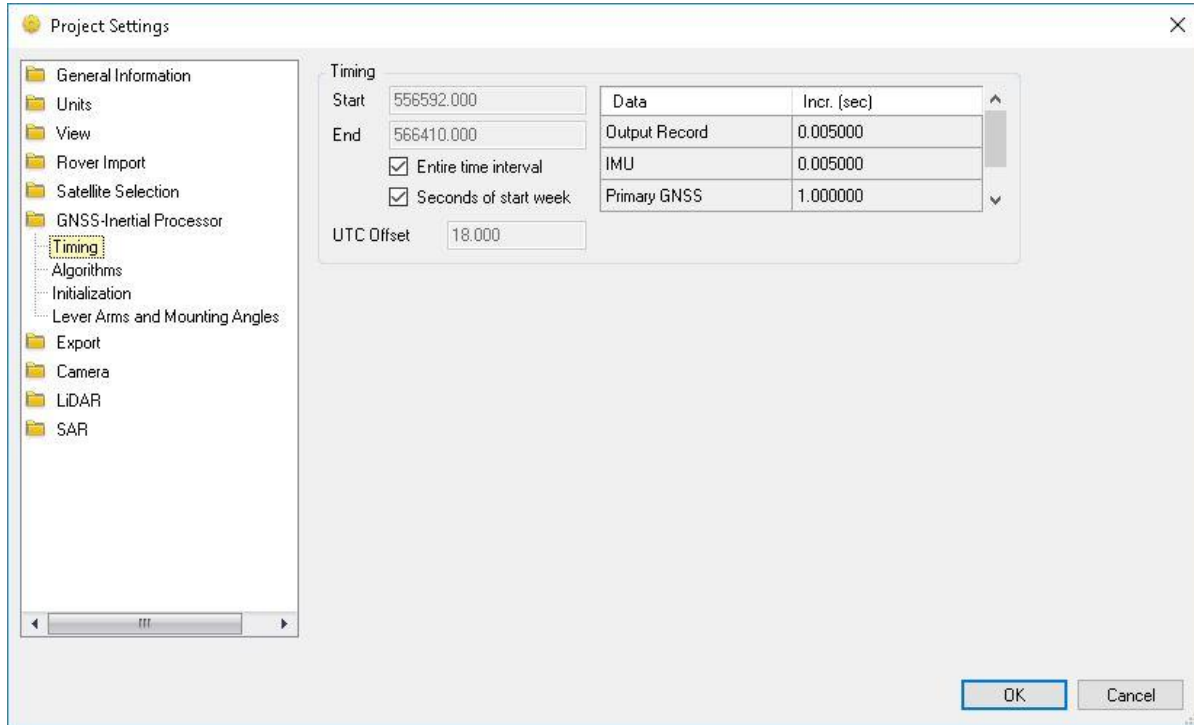
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LIDAR
- SAR

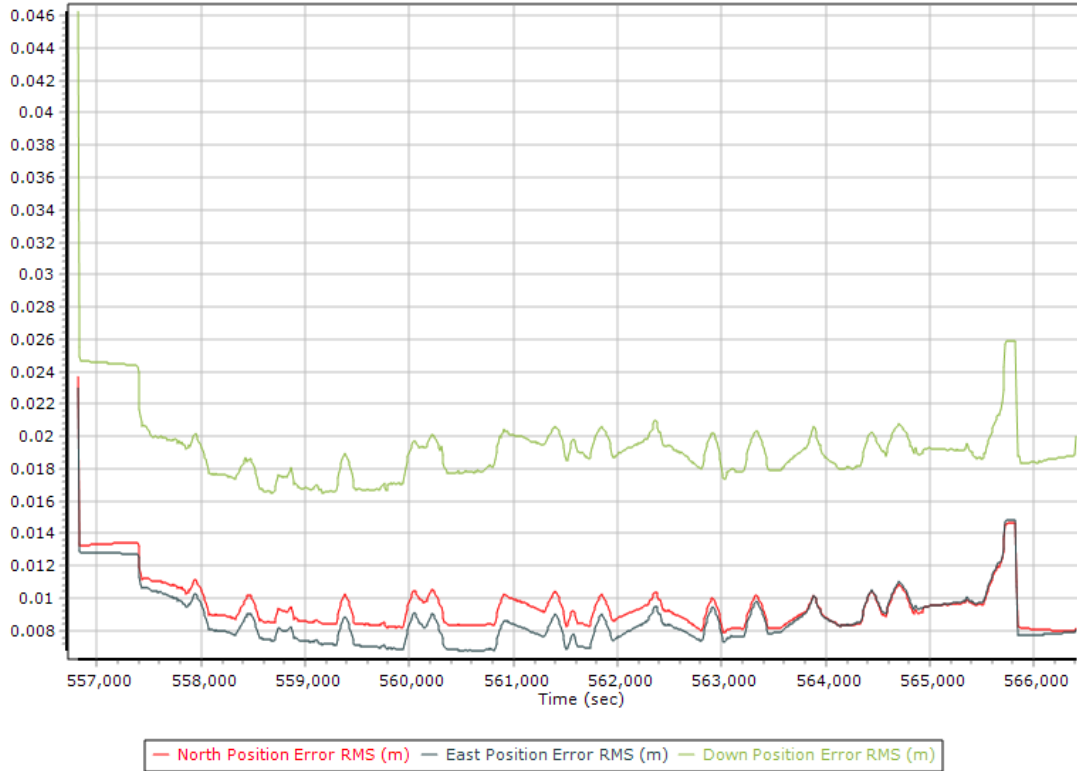
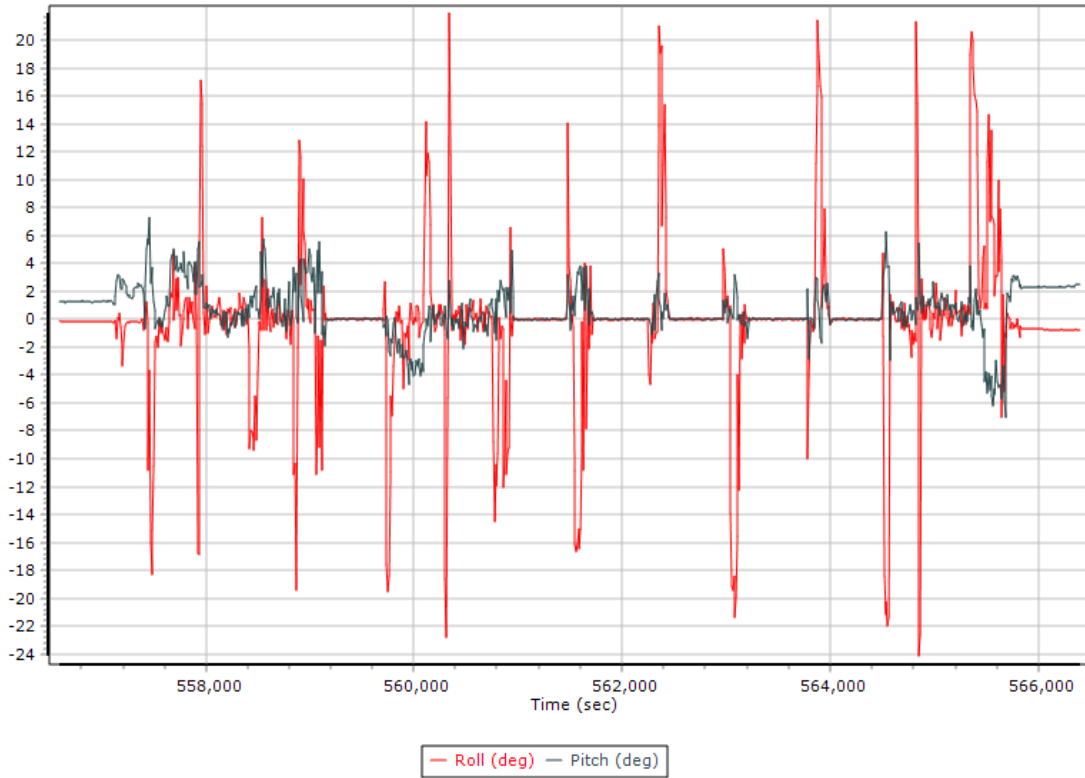
Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.049 m	0.003 m	-1.230 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

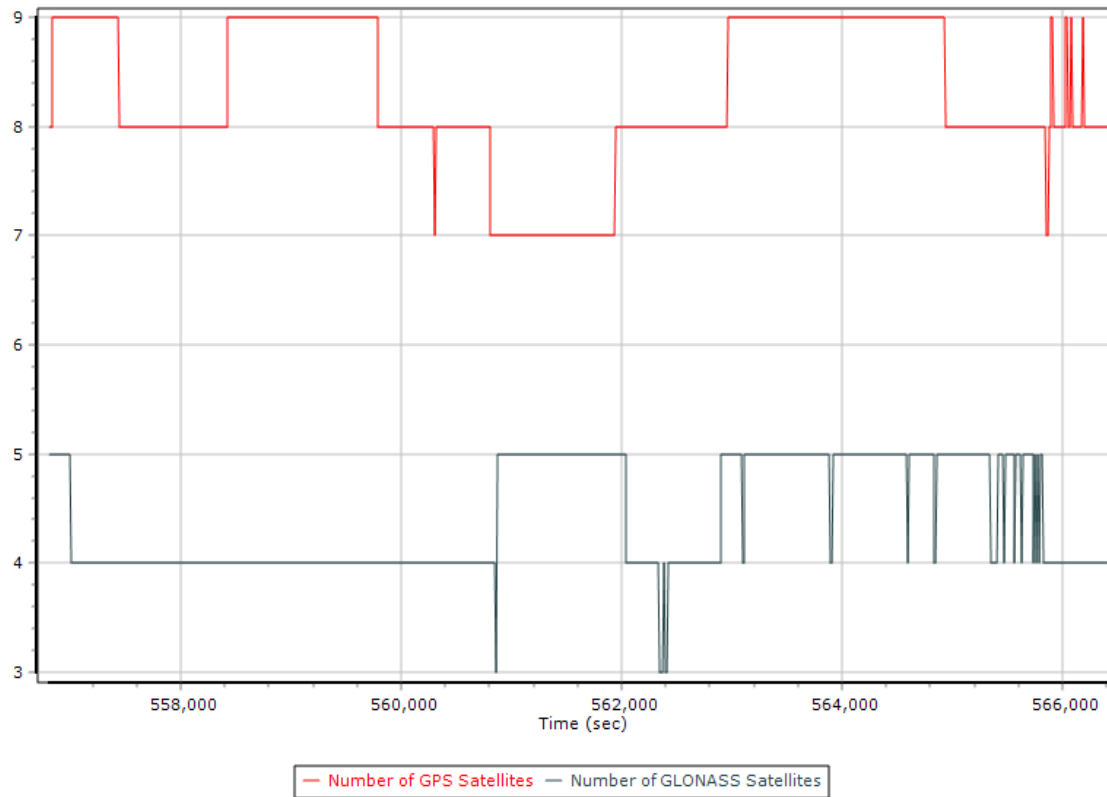
Standard Deviation: <3cm 10cm 50cm 1m 10m

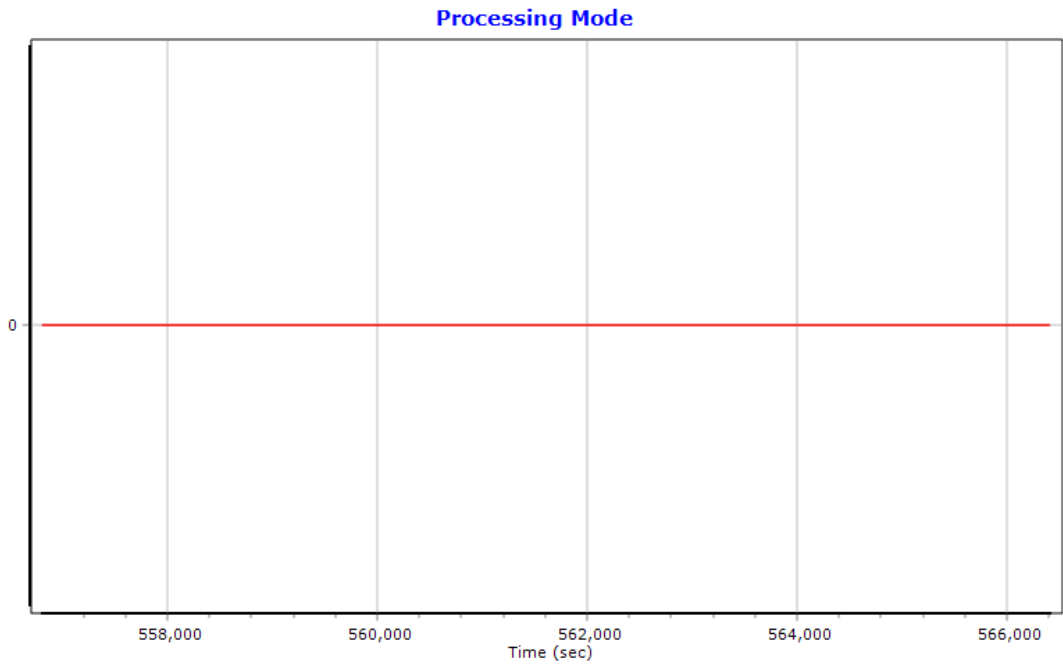
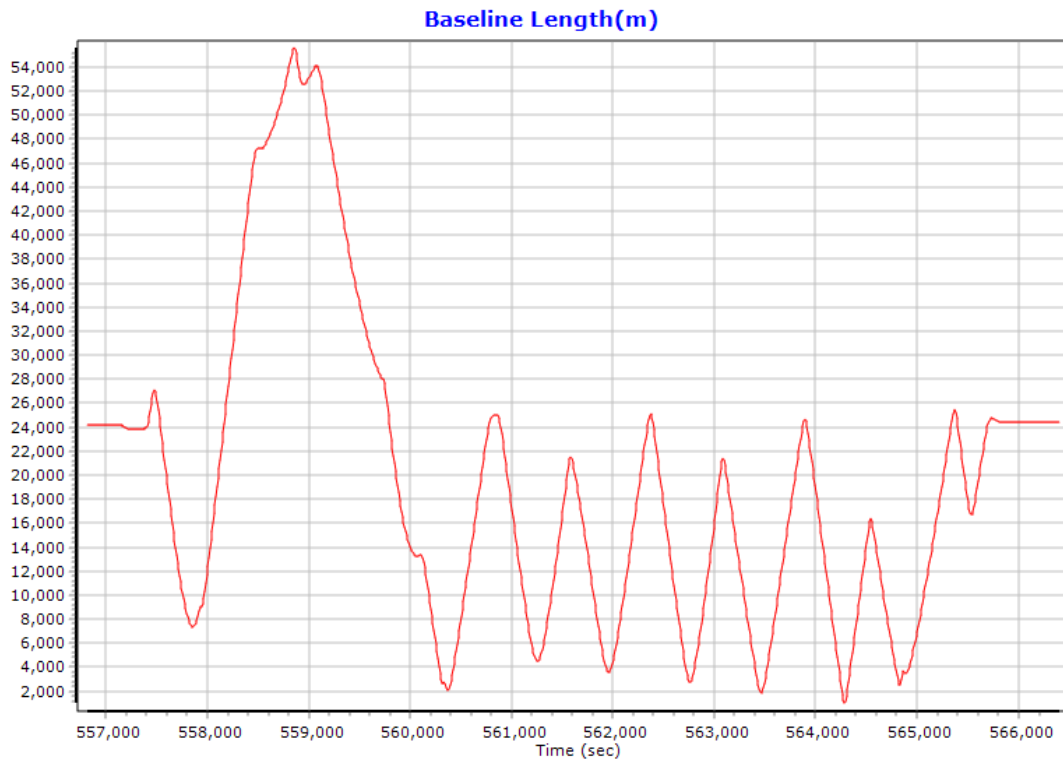
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

OK Cancel





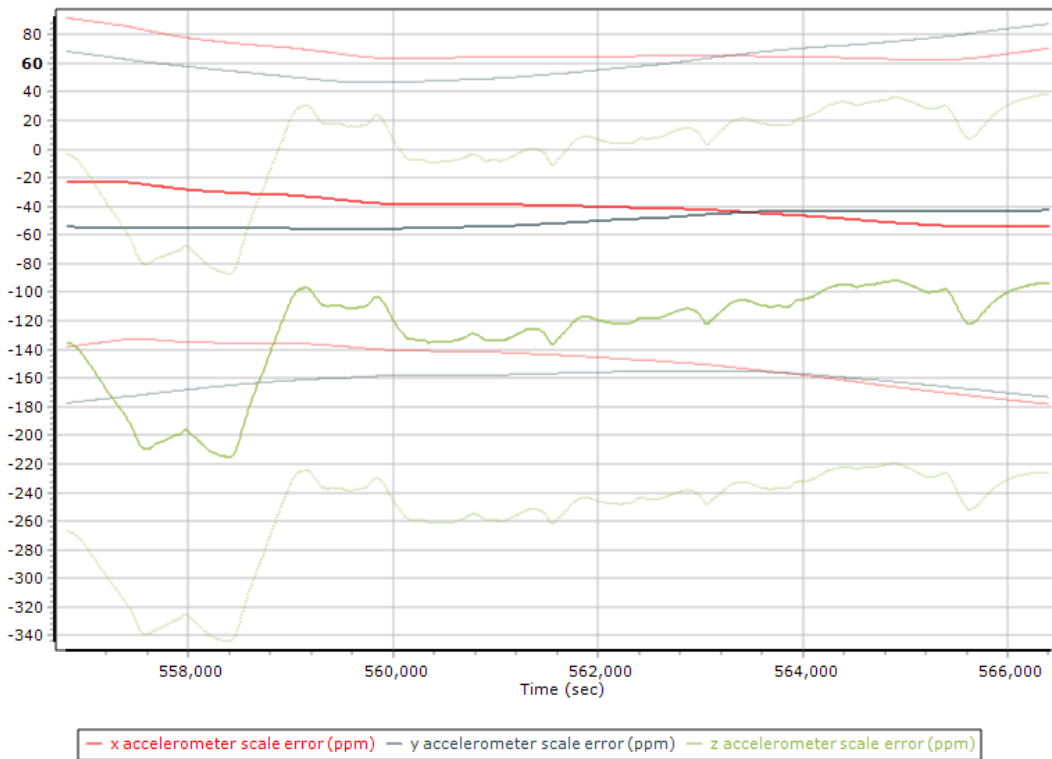
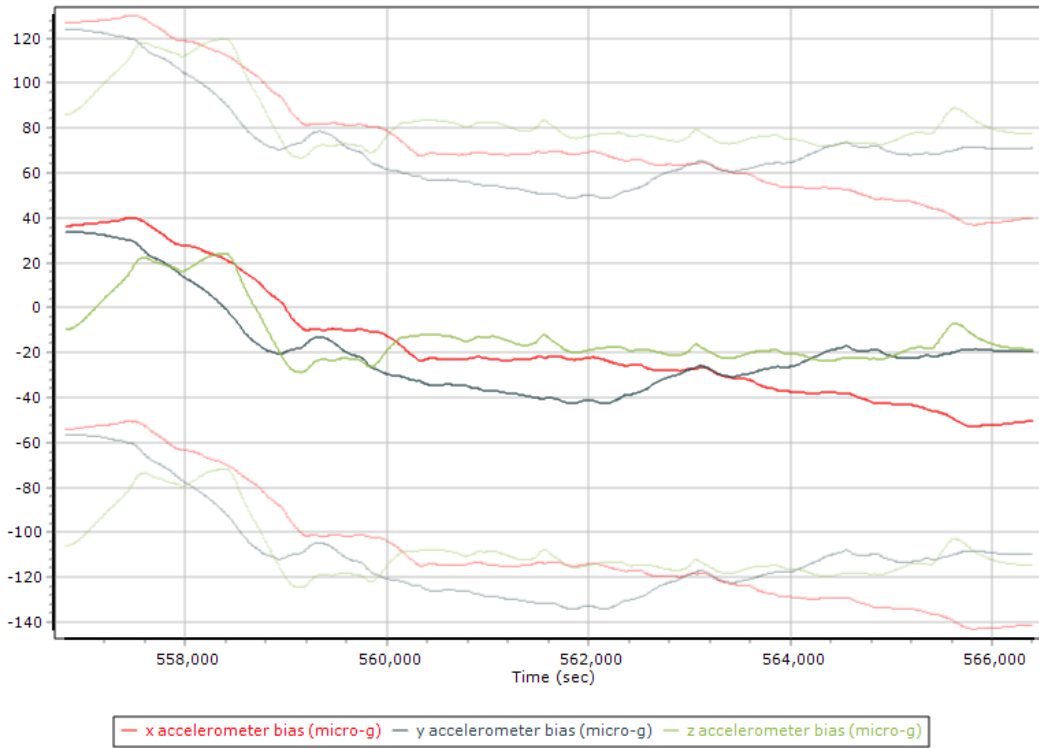


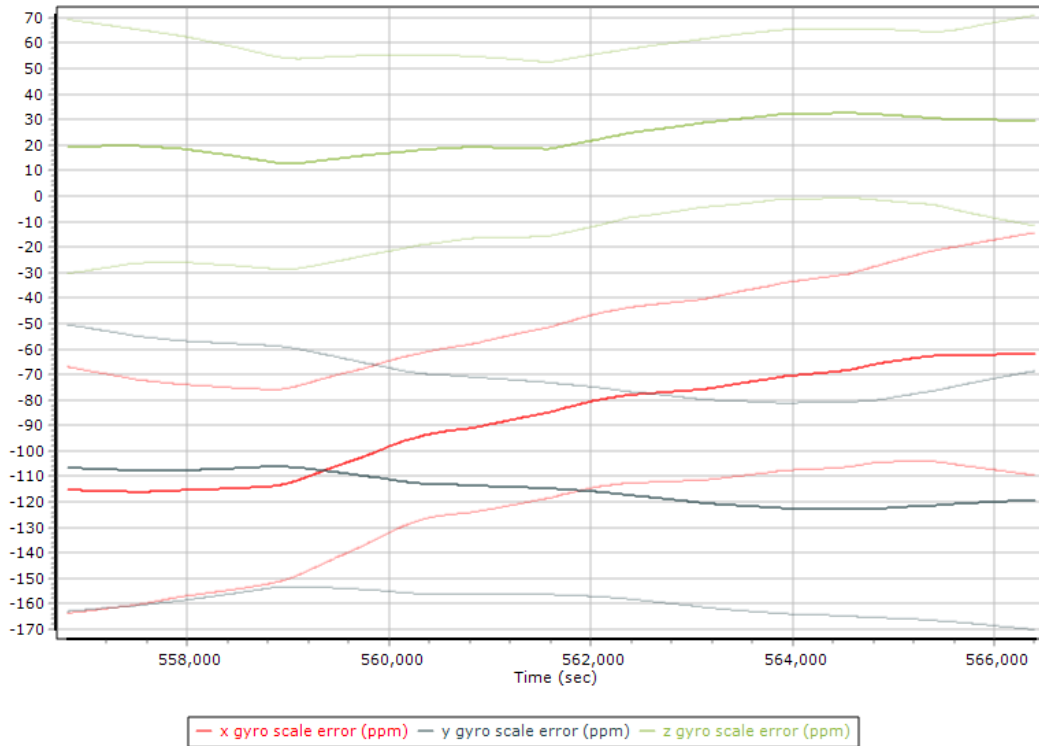
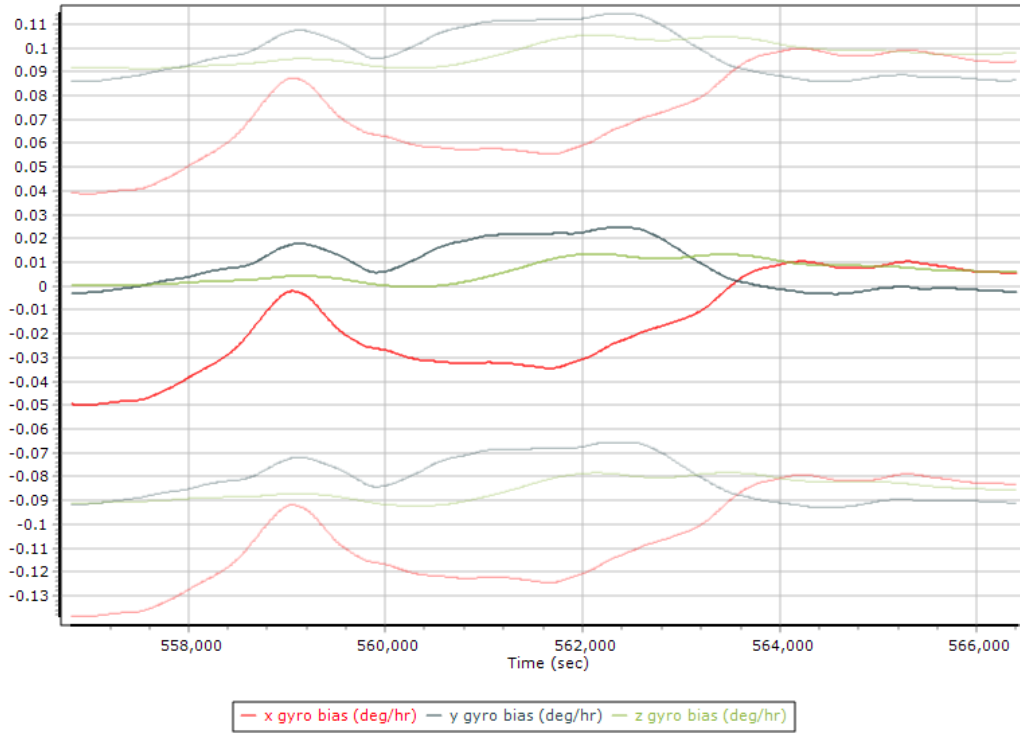


Forward Reverse

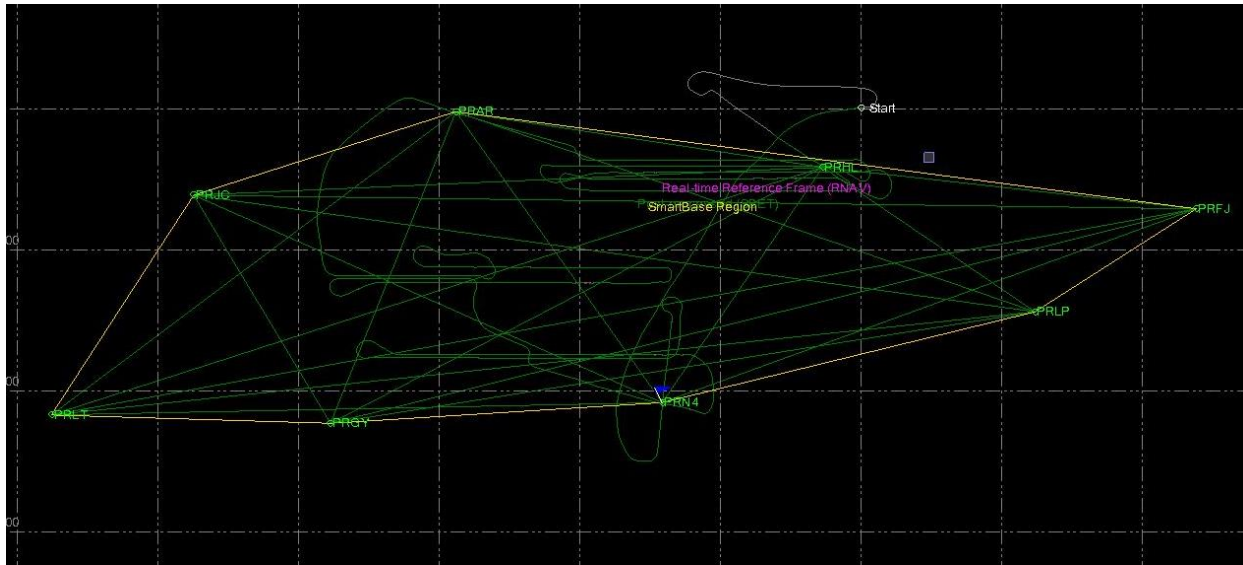
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





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Project Settings

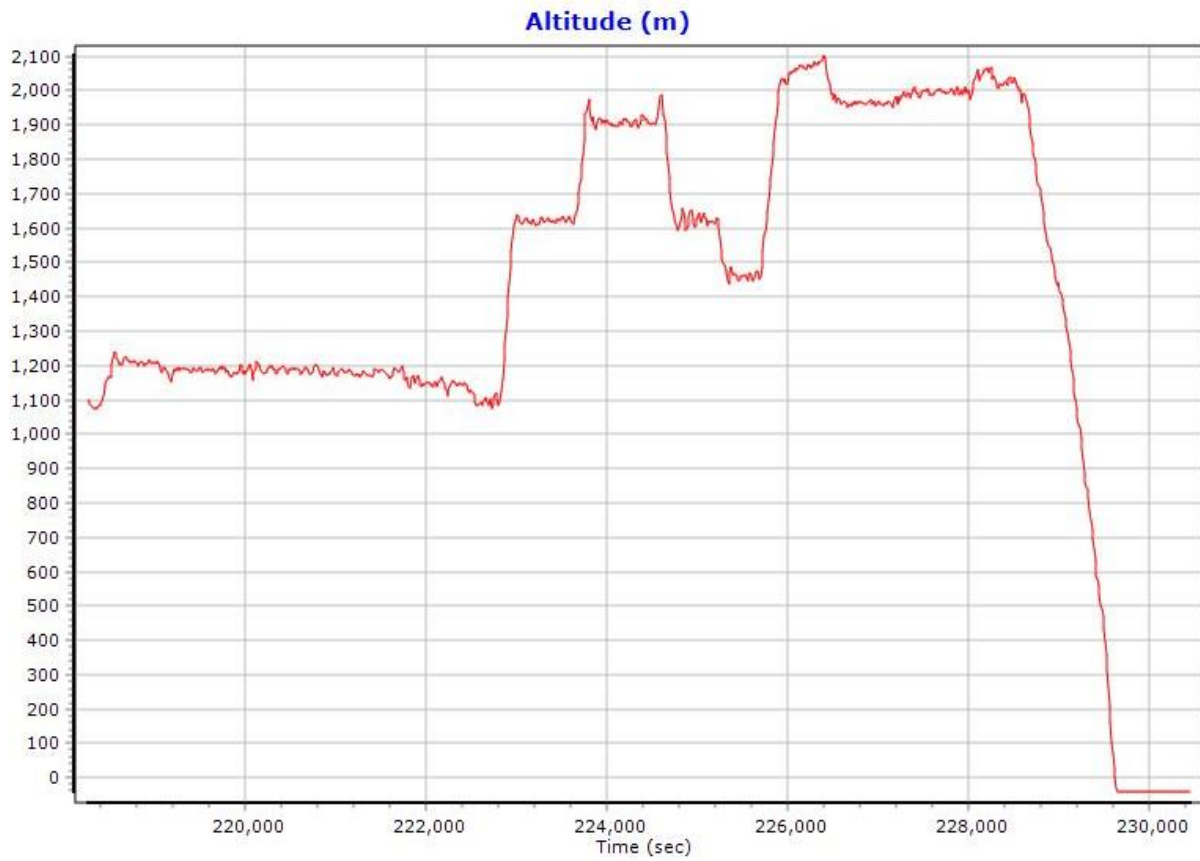
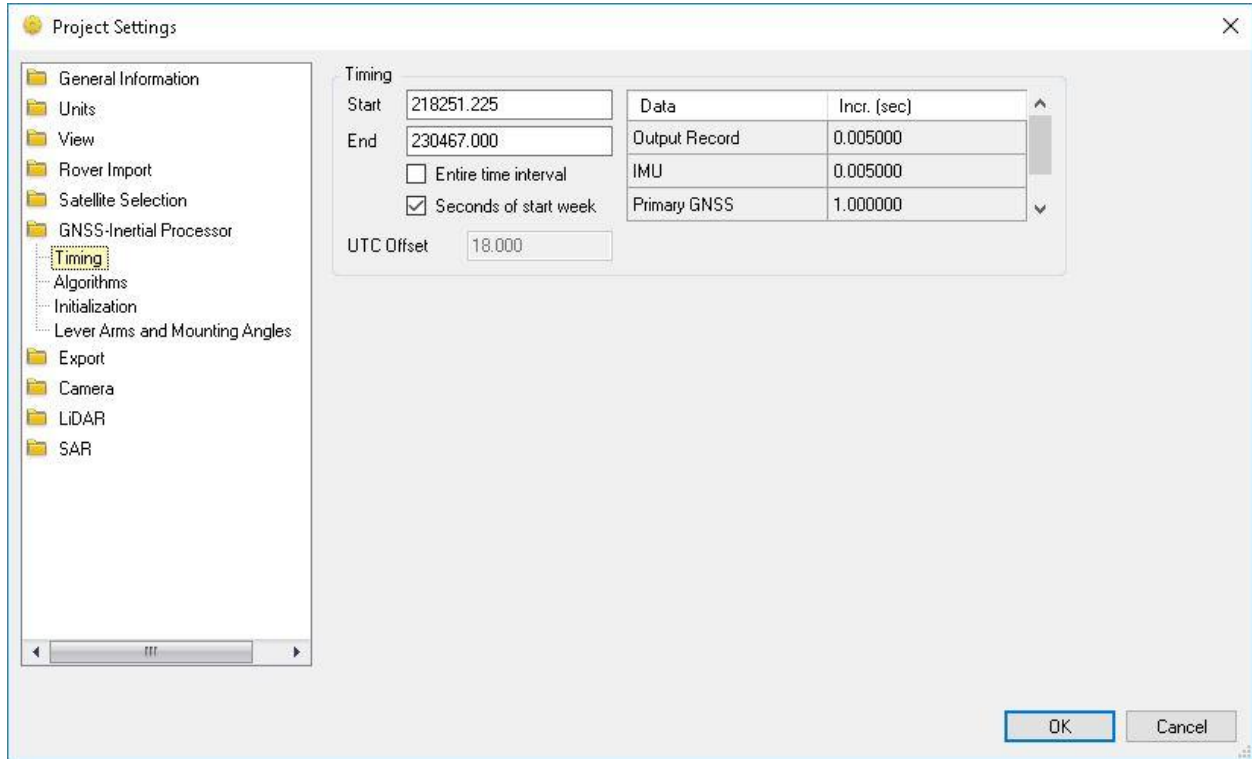
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LIDAR
- SAR

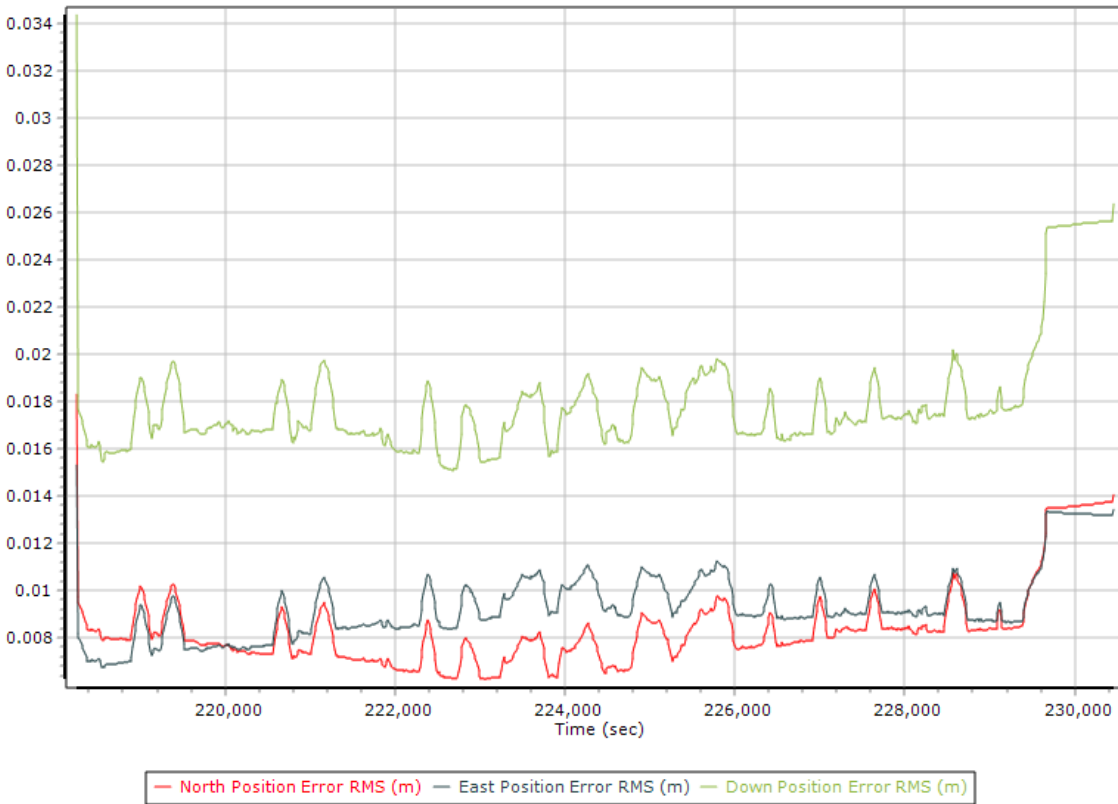
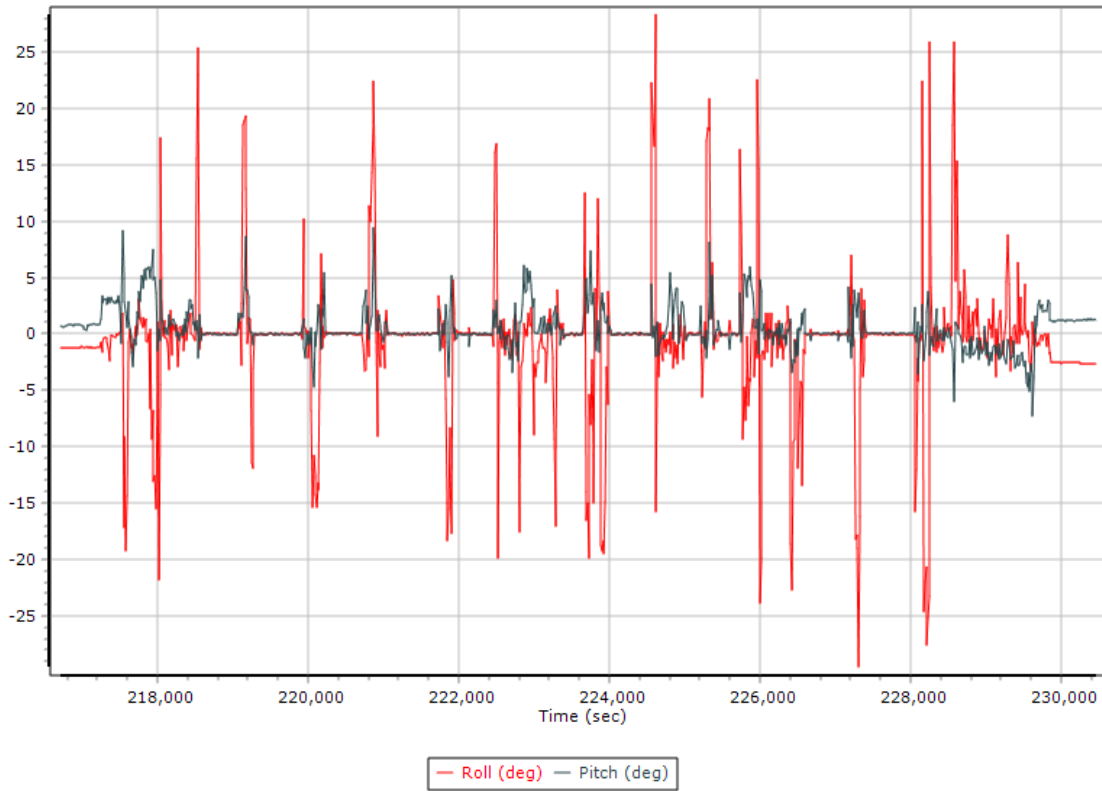
Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.049 m	0.003 m	-1.230 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

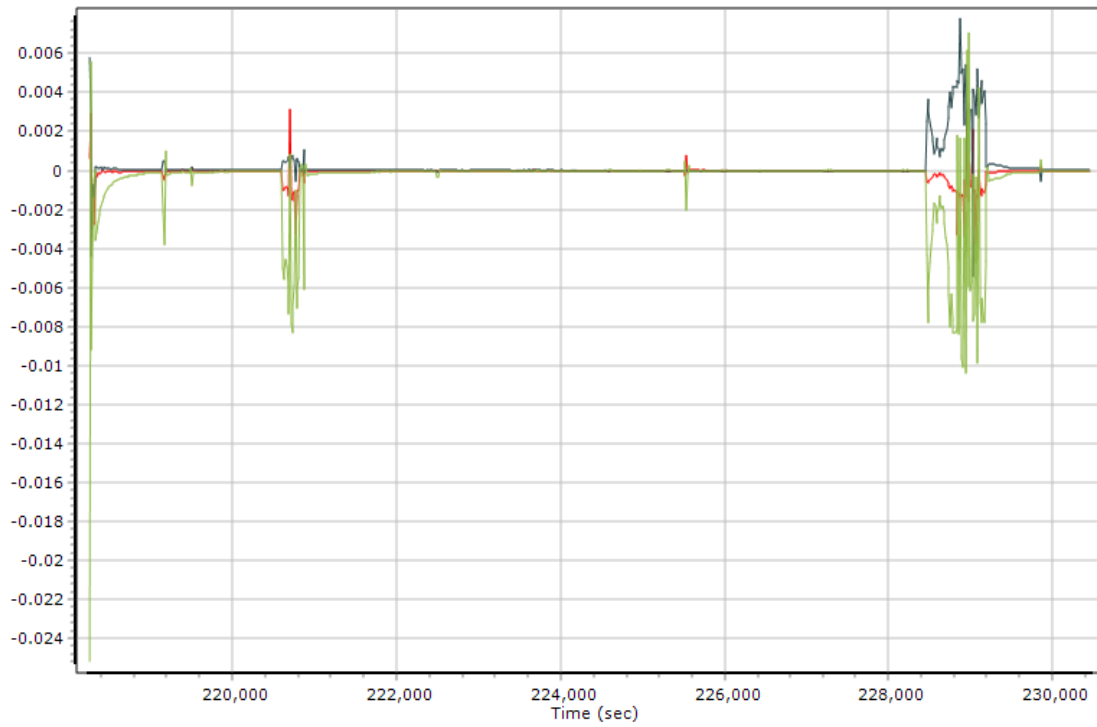
Standard Deviation: <3cm 10cm 50cm 1m 10m

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

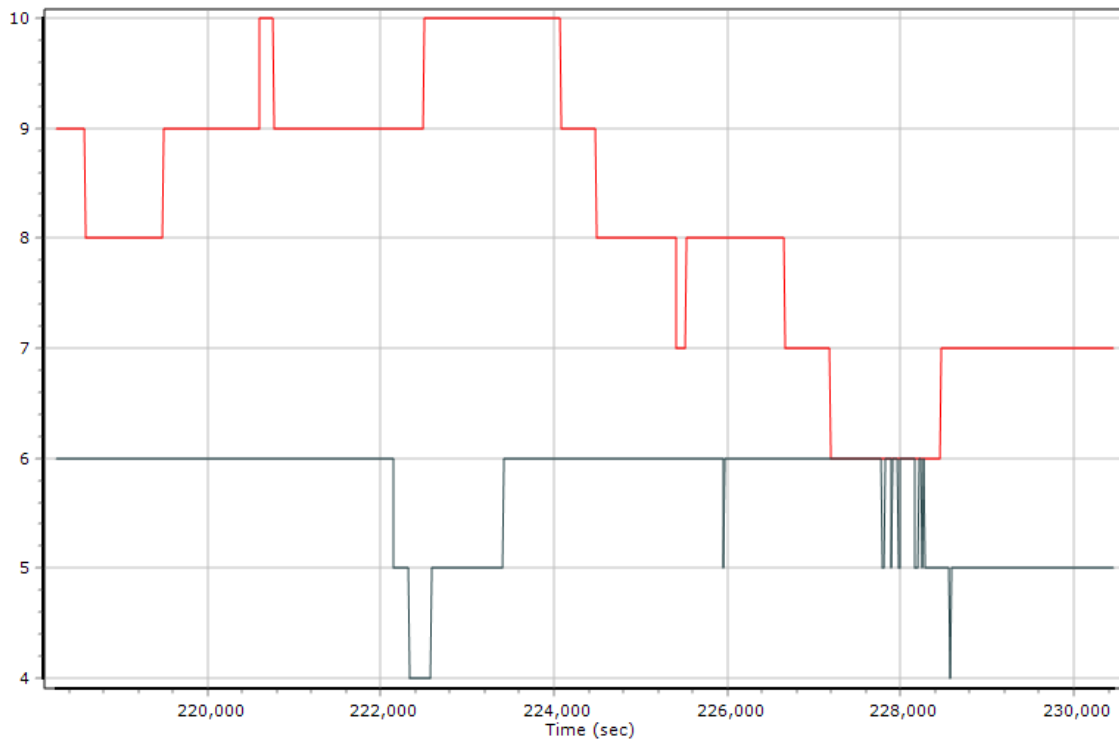
OK Cancel



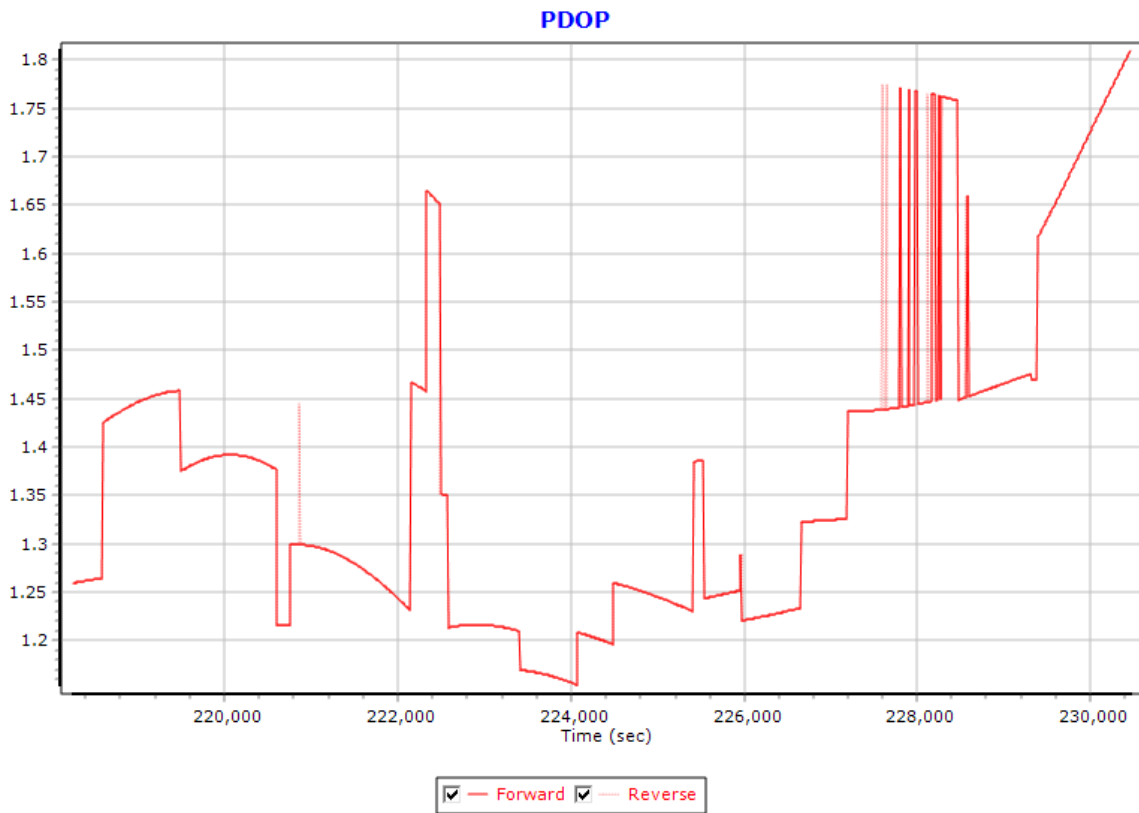
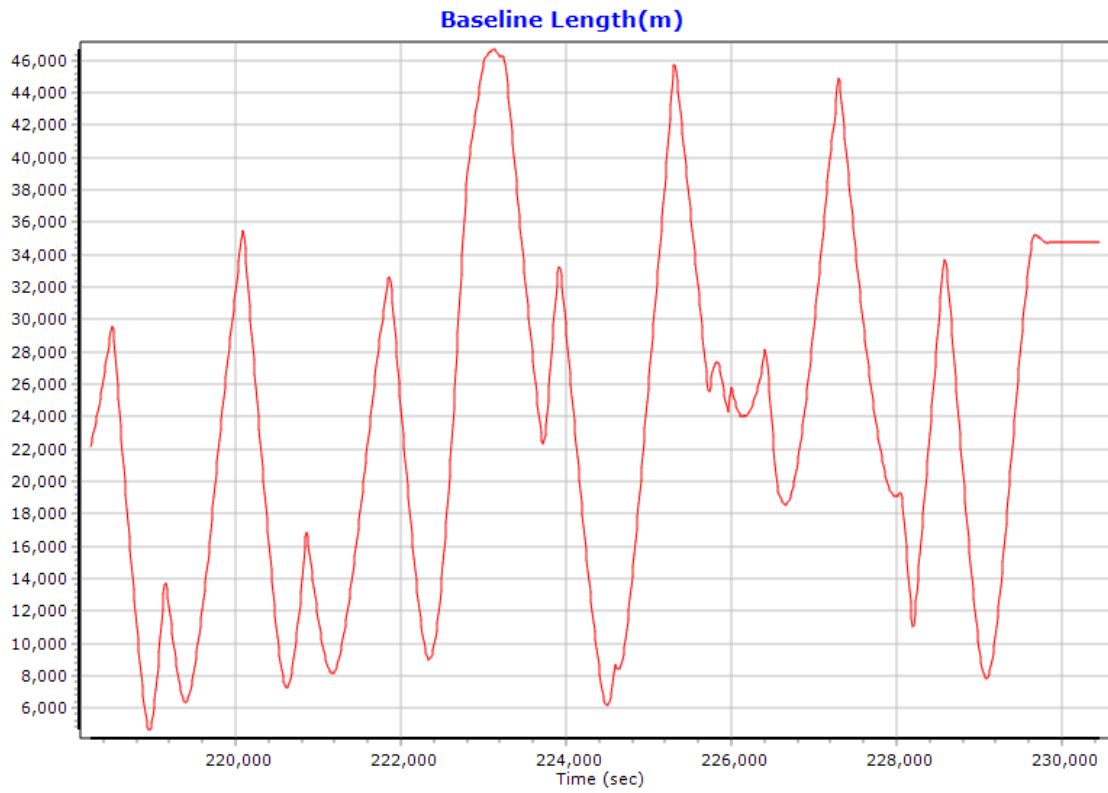




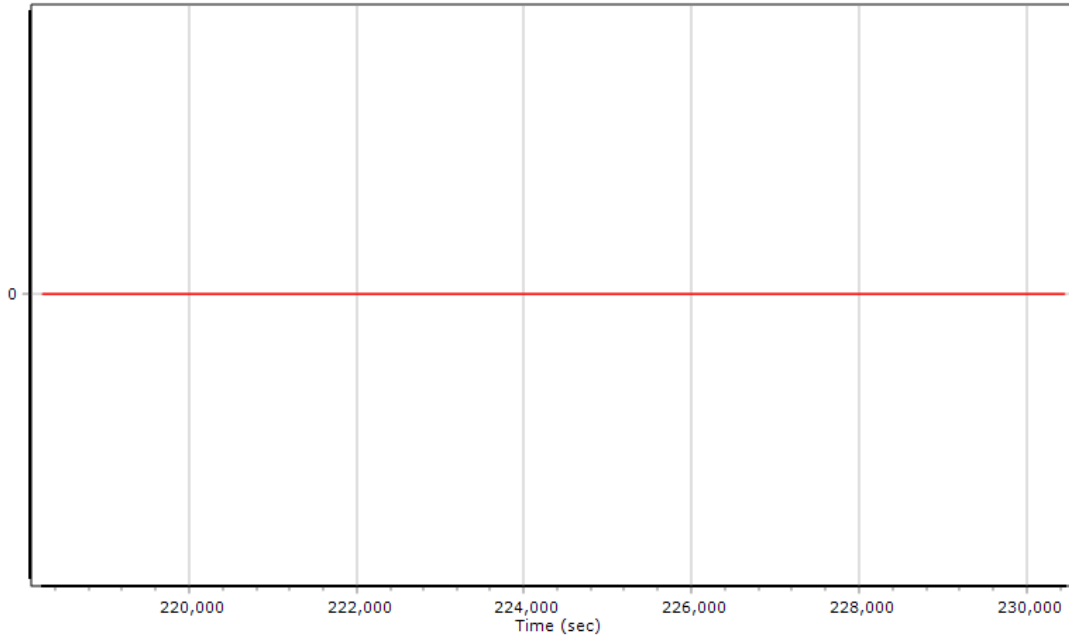
— North (m) — East (m) — Down (m) — DR mode



— Number of GPS Satellites — Number of GLONASS Satellites



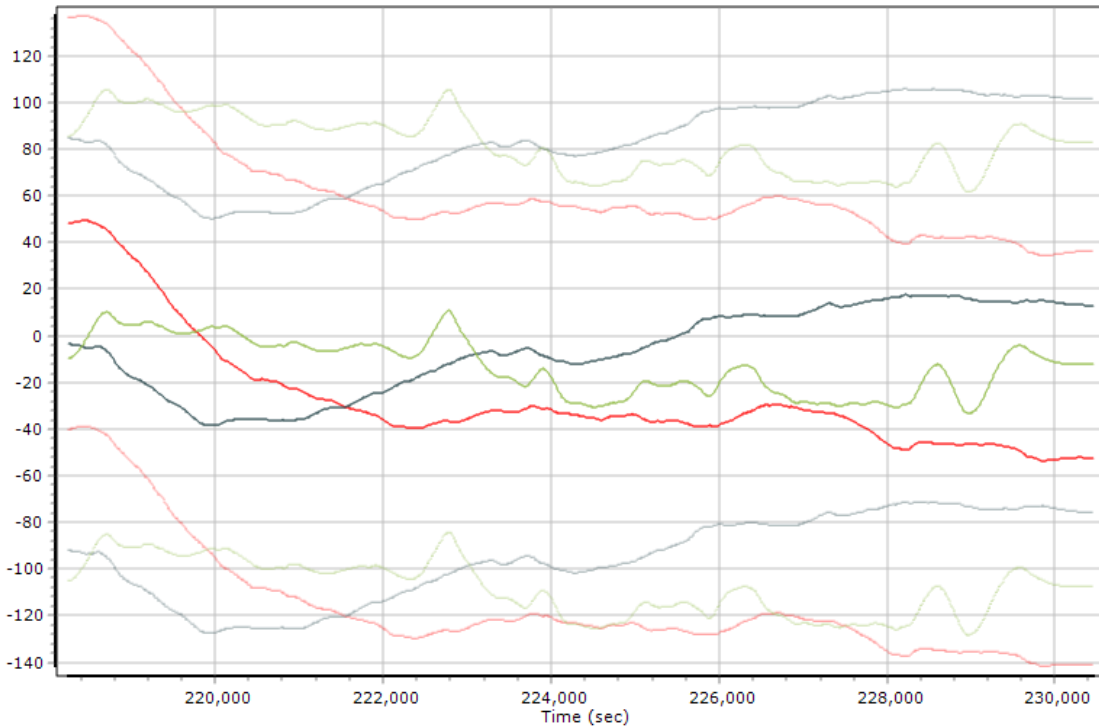
Processing Mode



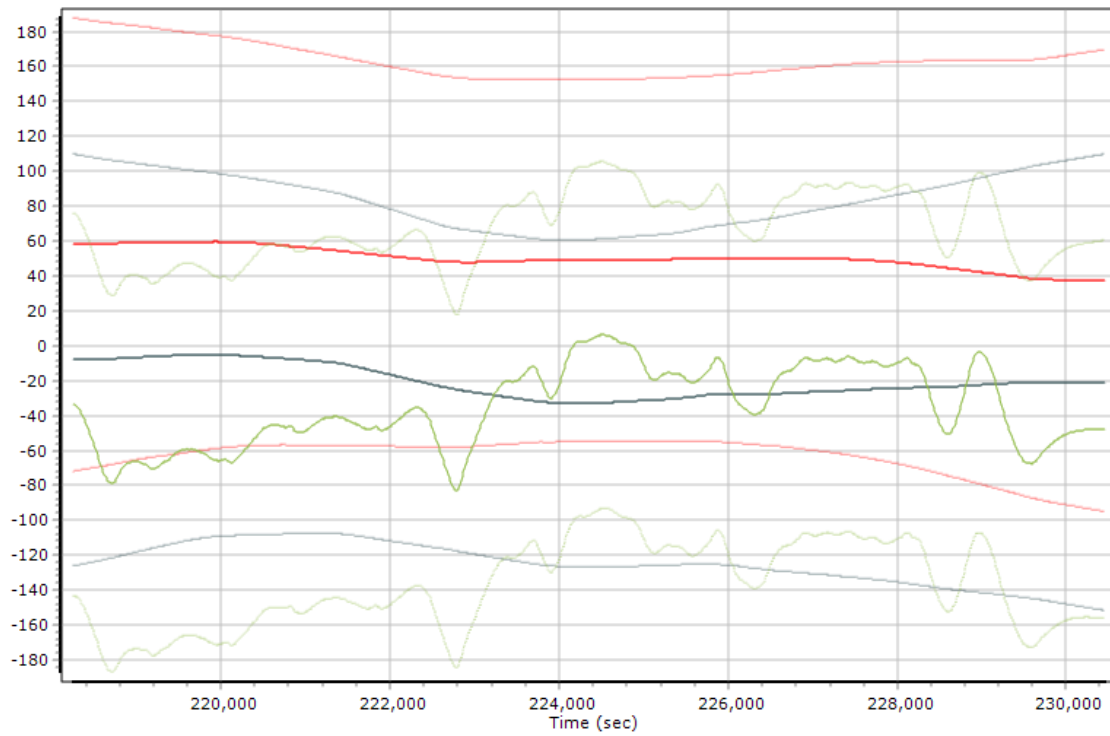
Forward Reverse

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

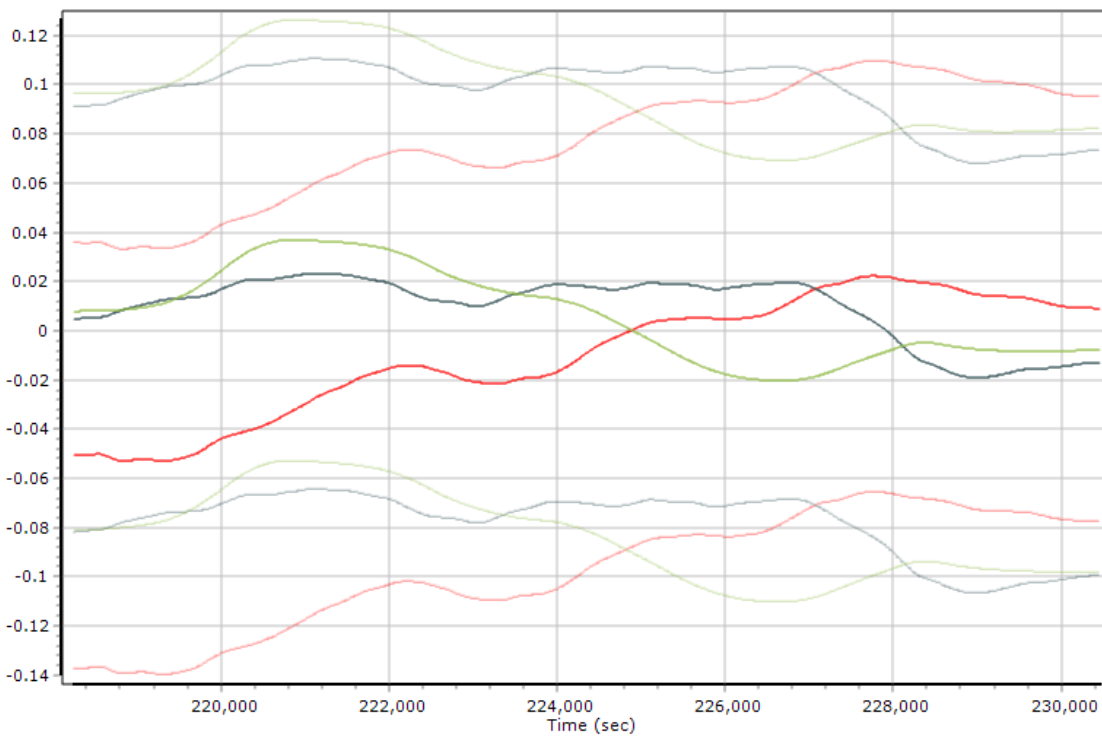
Sensor Errors



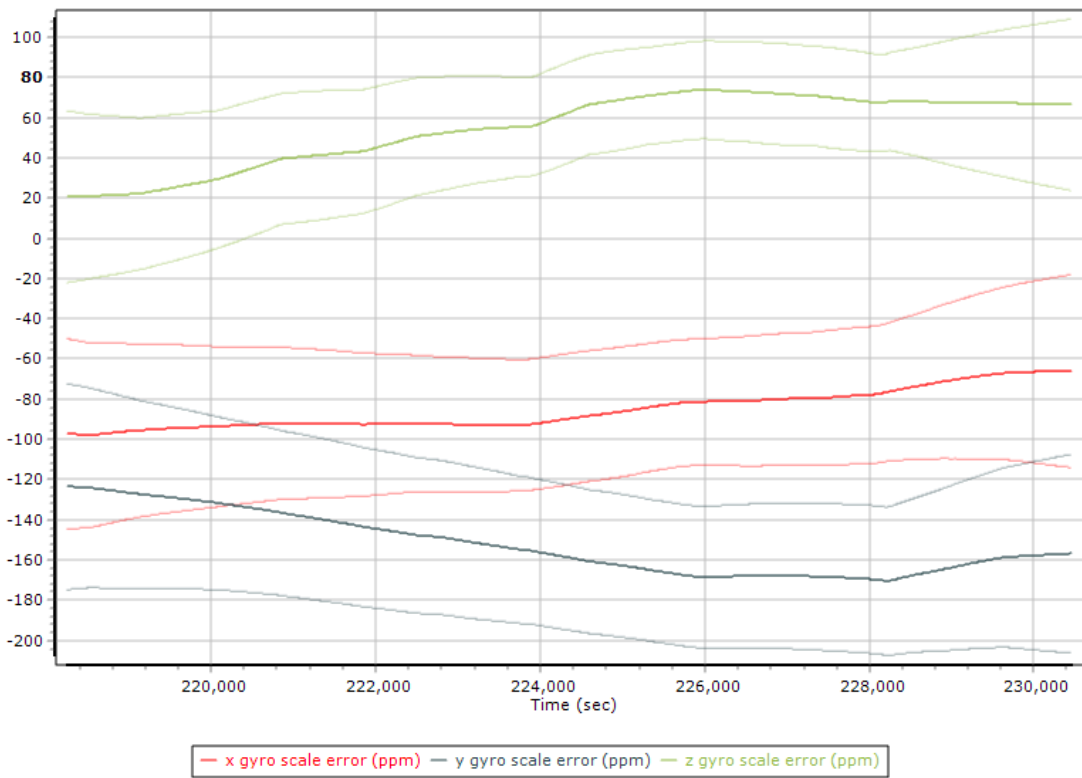
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



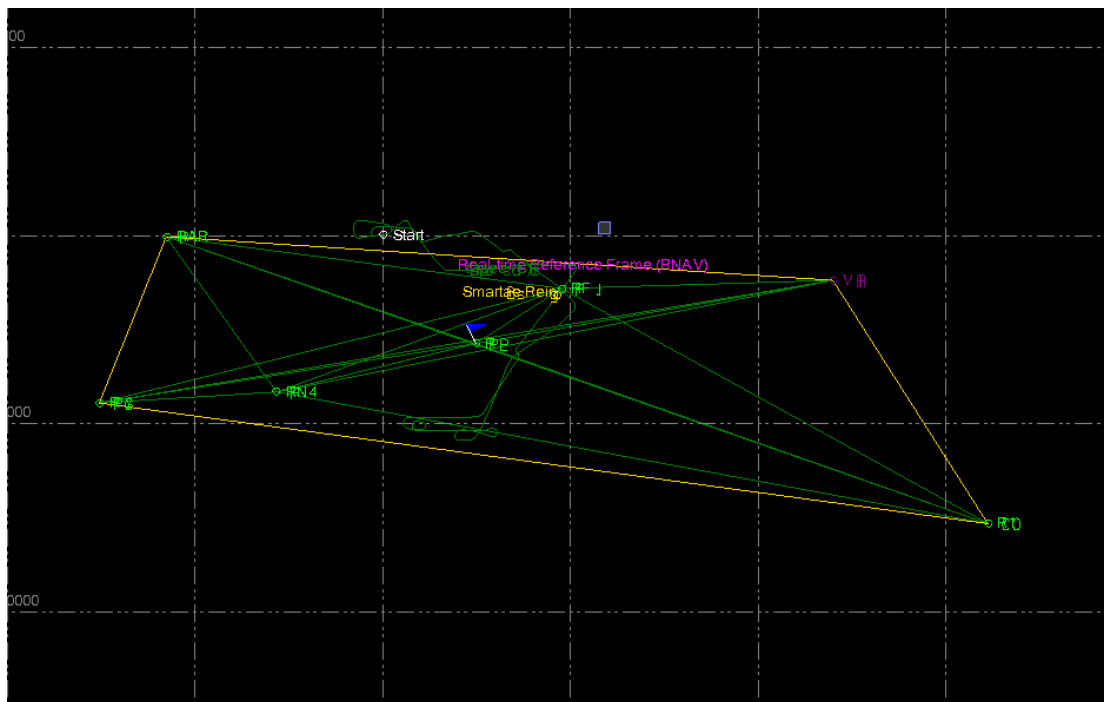
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

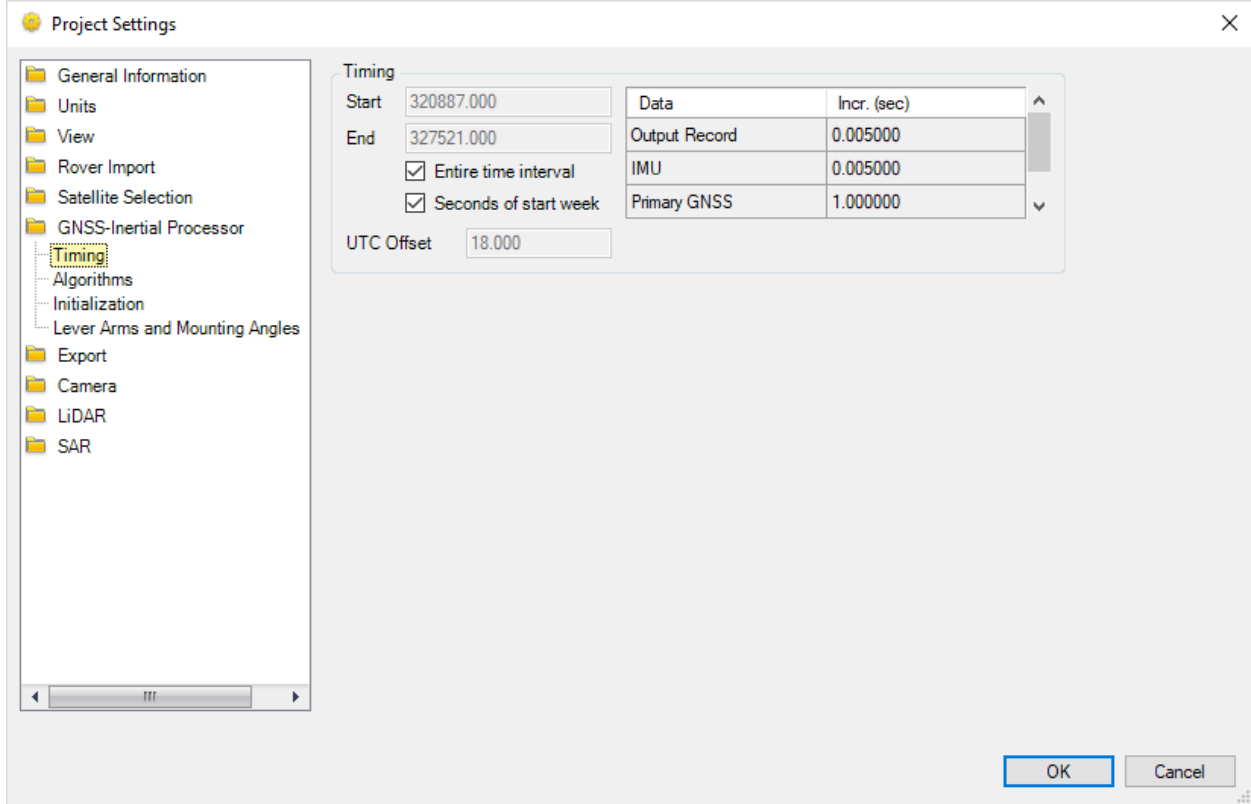
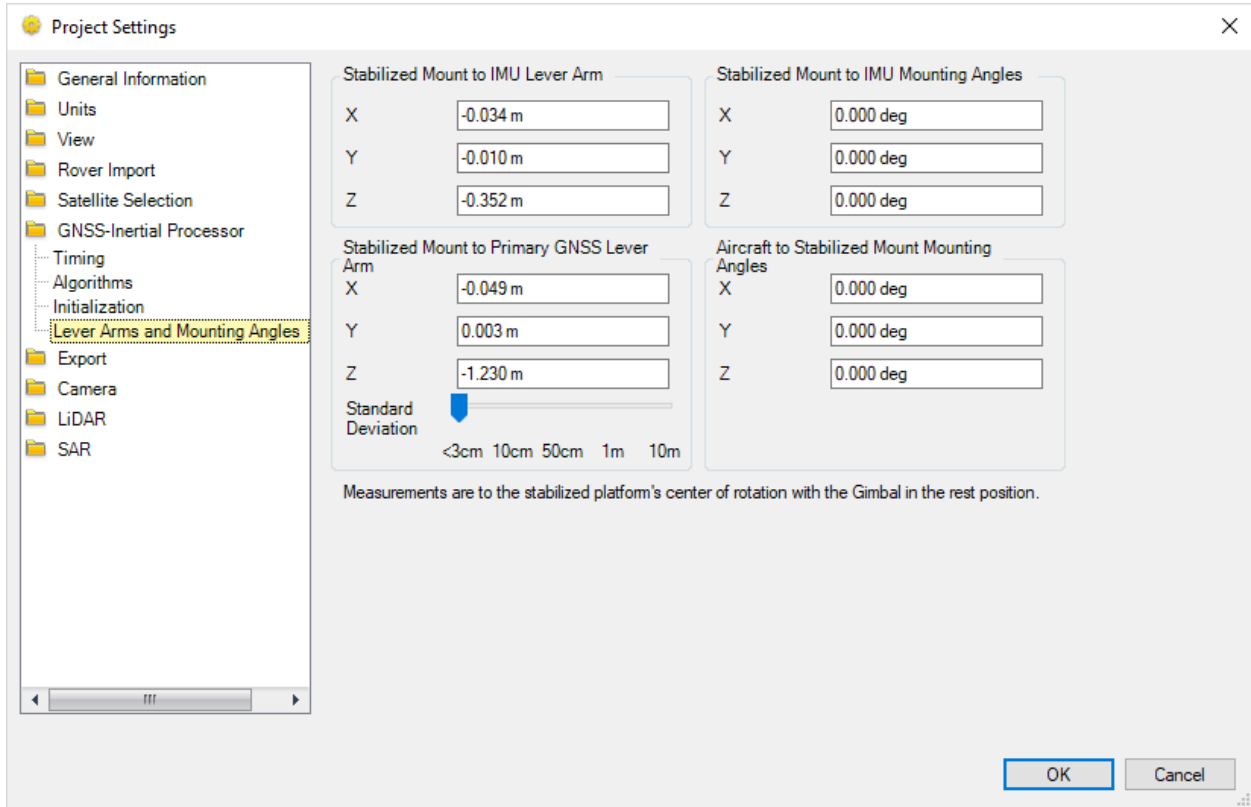


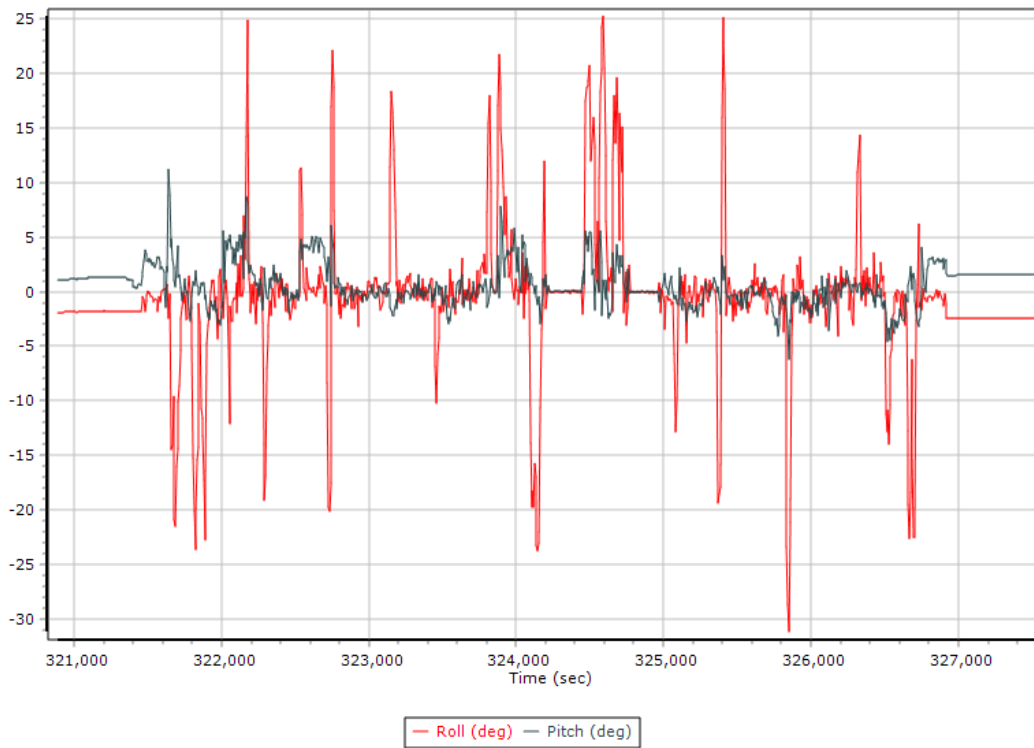
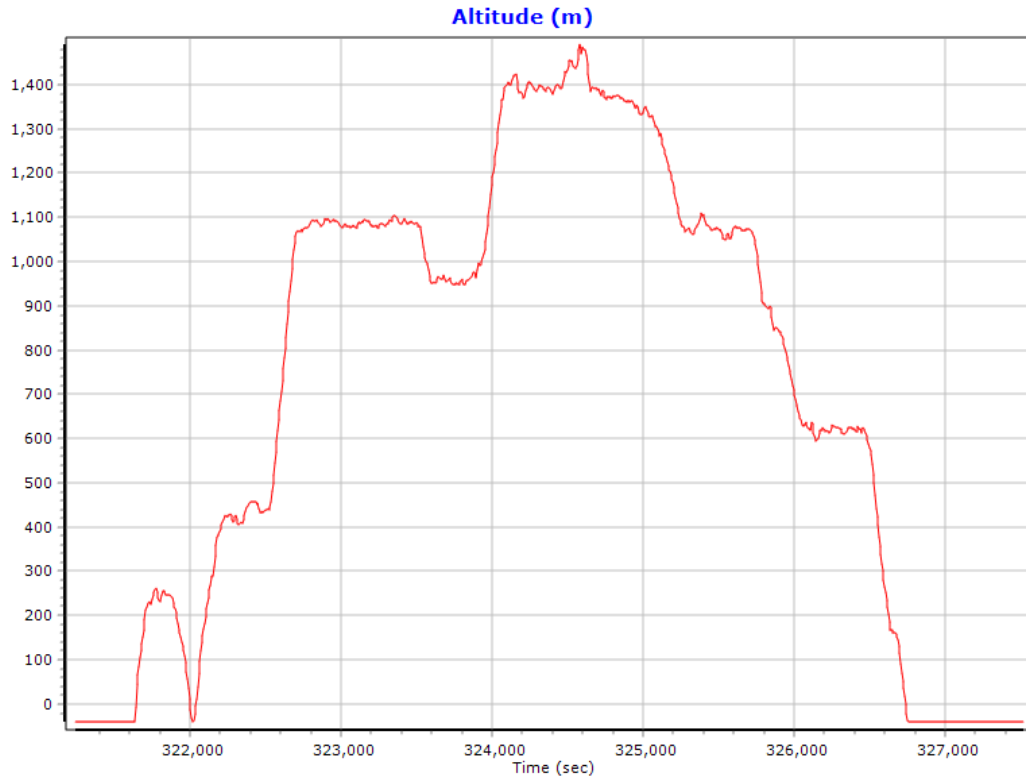
— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

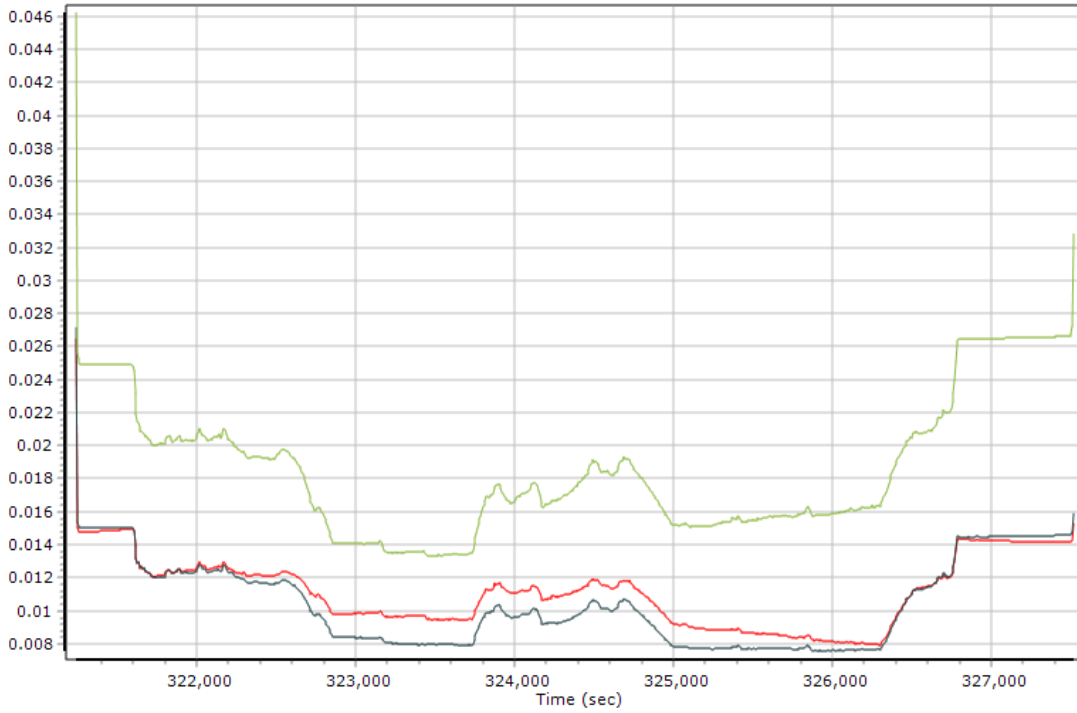


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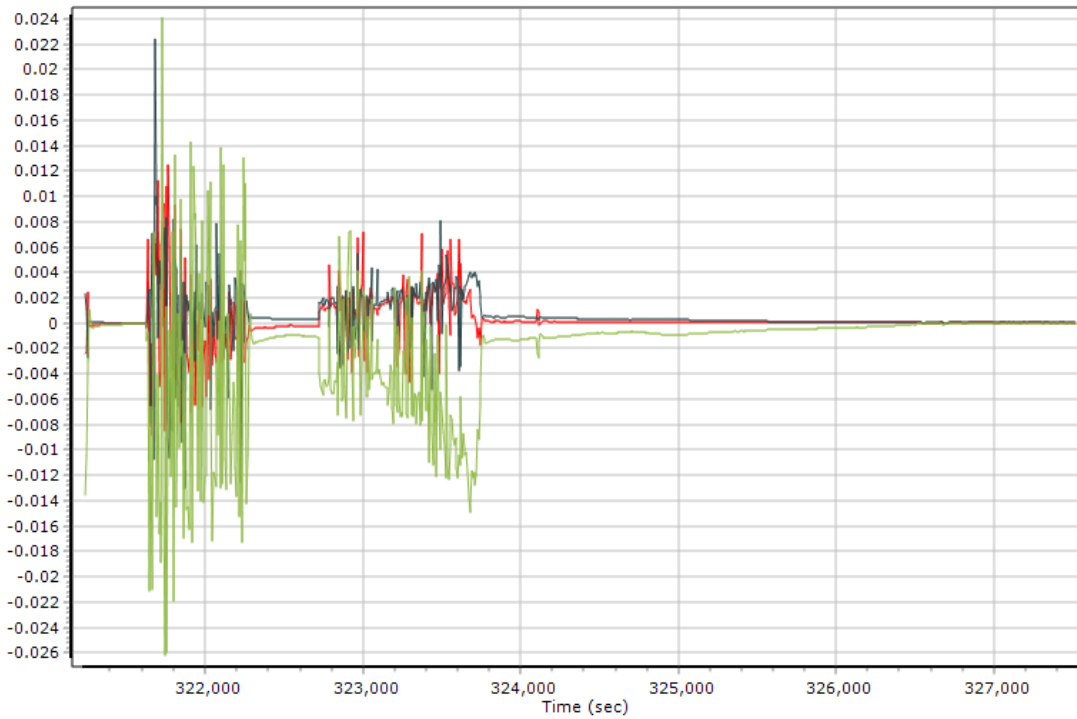




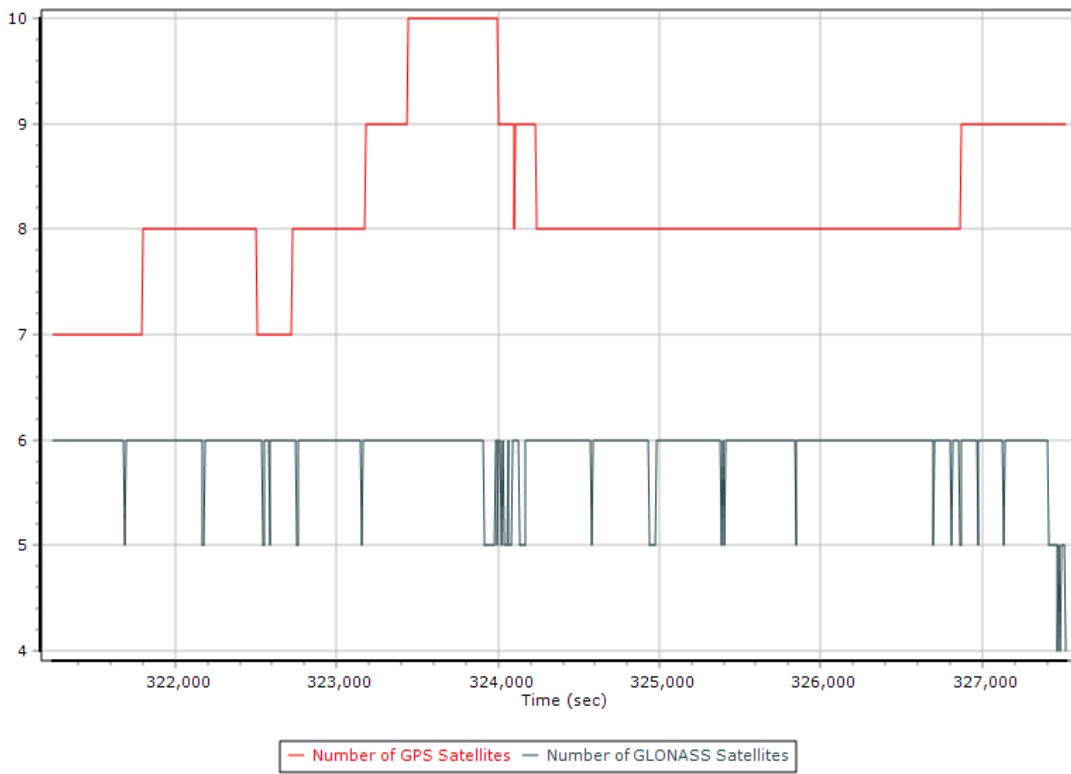




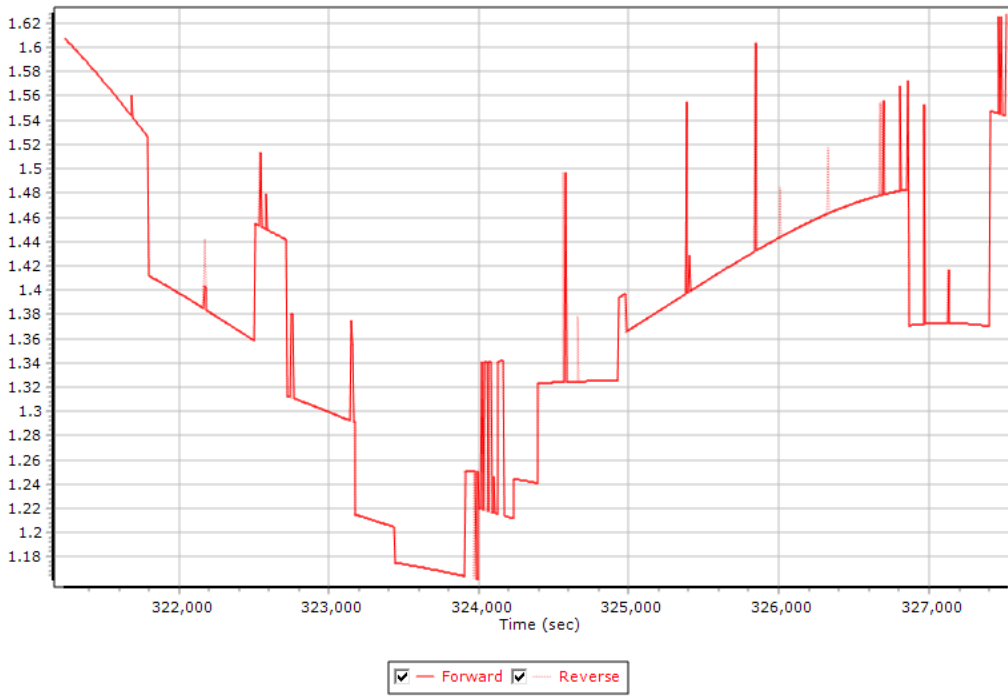
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)

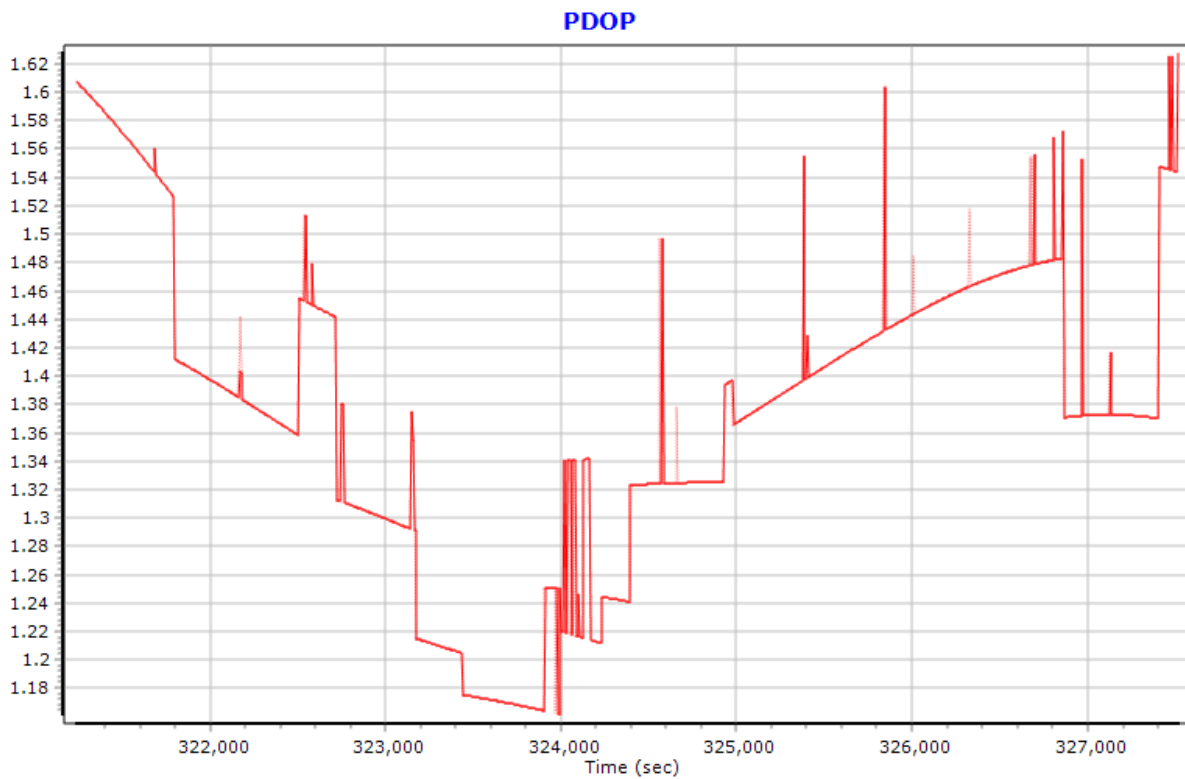
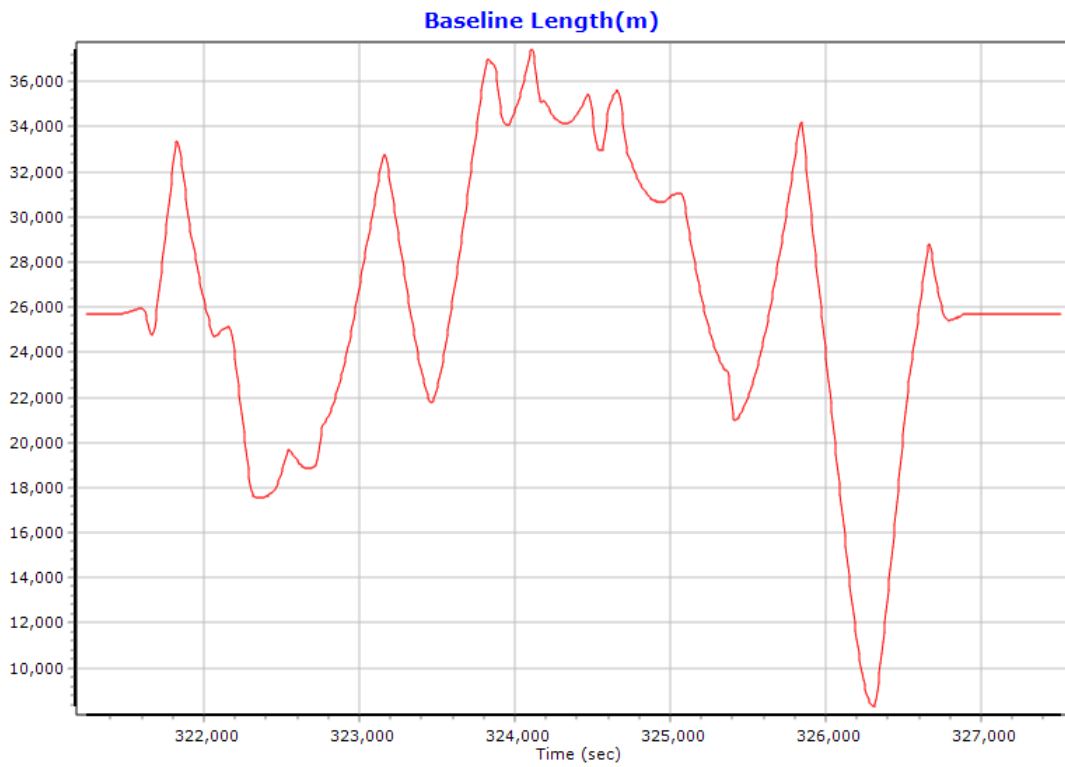


— North (m) — East (m) — Down (m) — DR mode



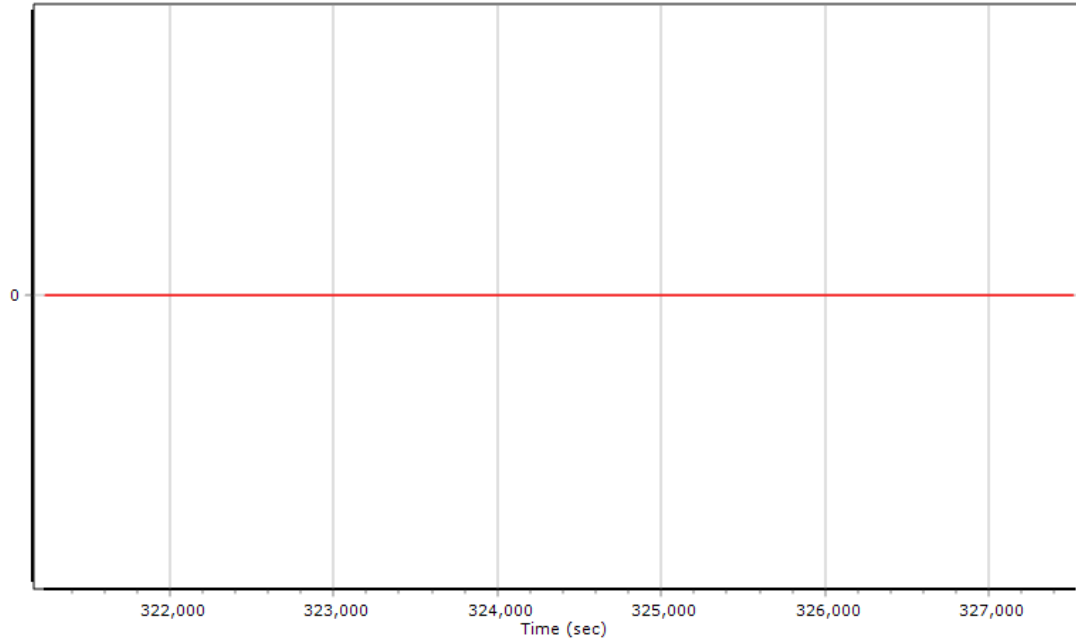
PDOP





Forward Reverse

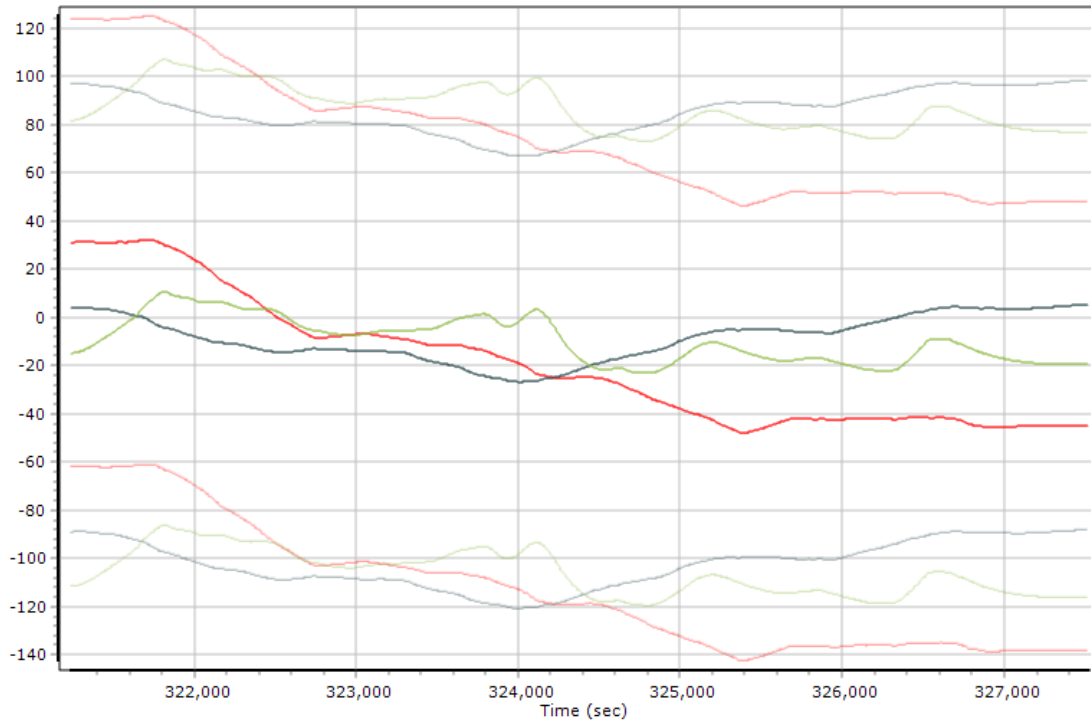
Processing Mode



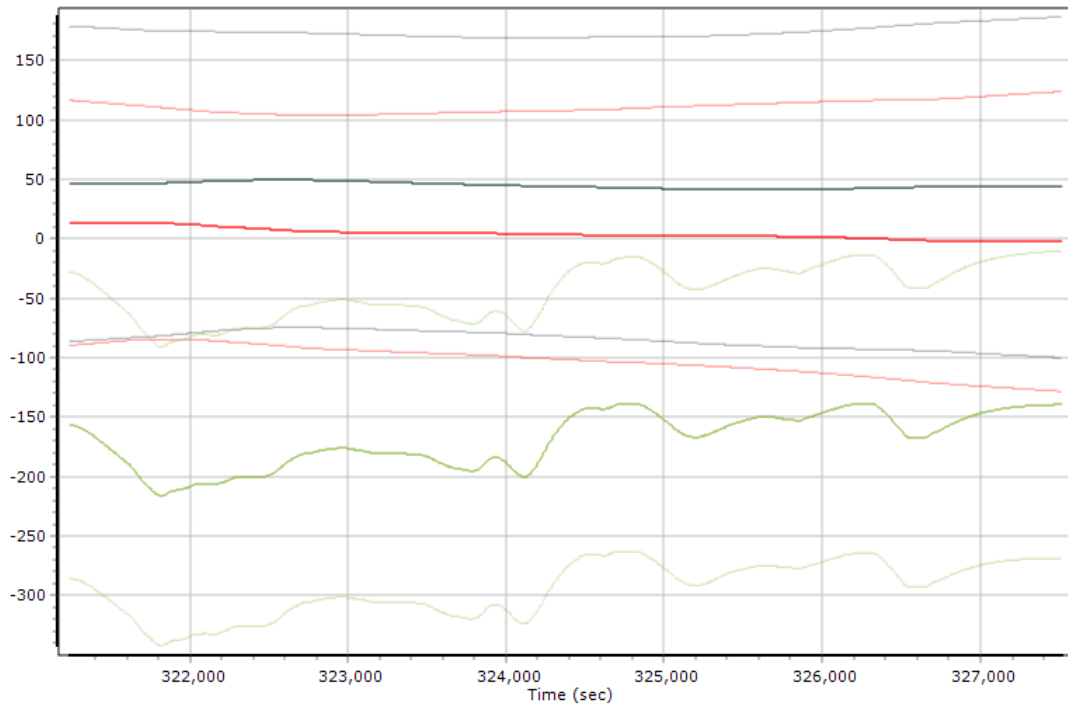
Forward Reverse

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

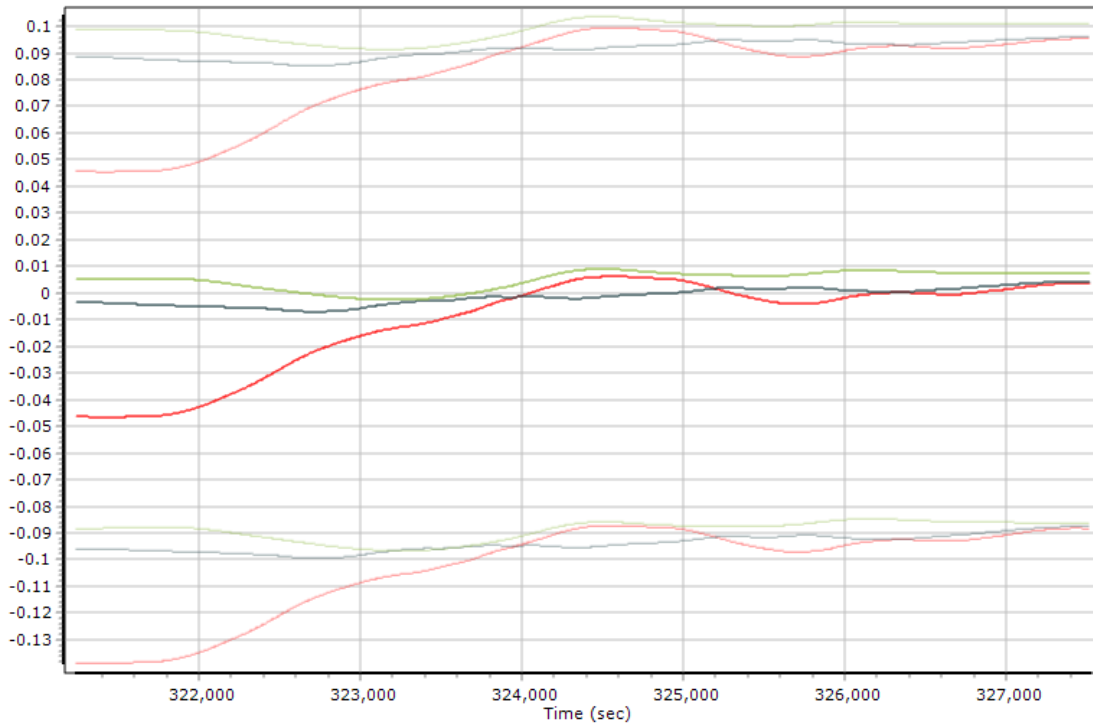
Sensor Errors



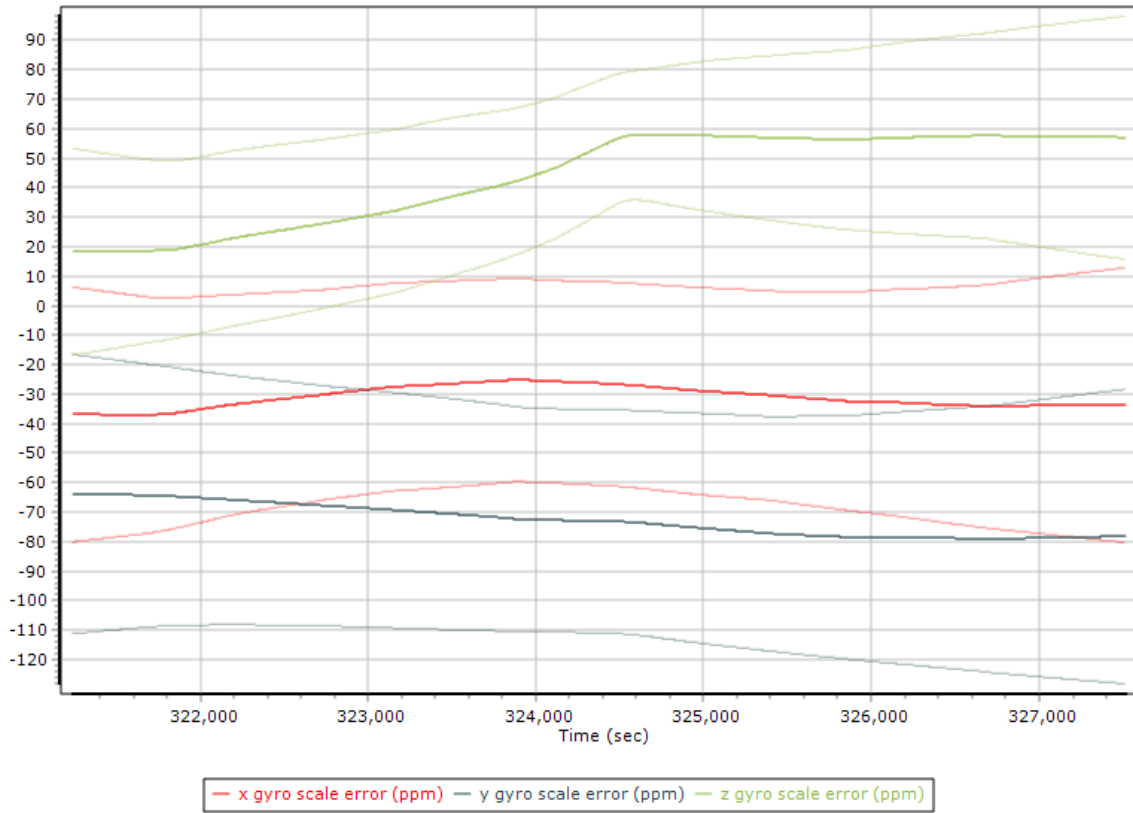
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



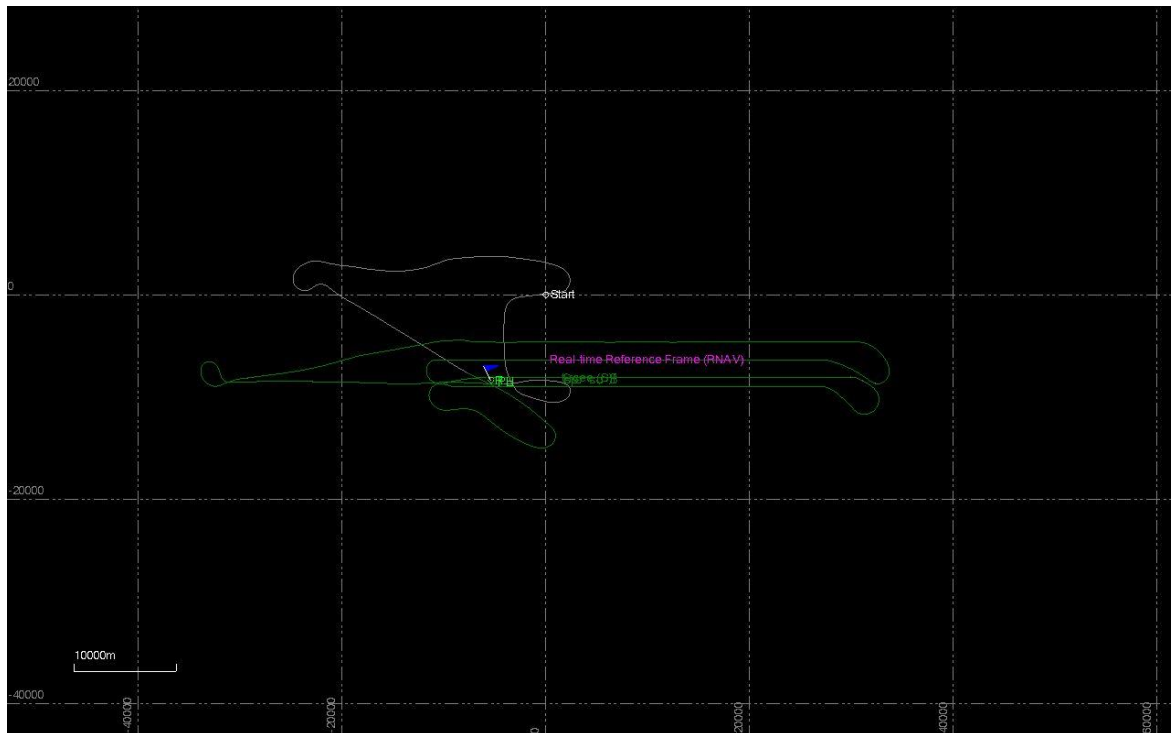
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

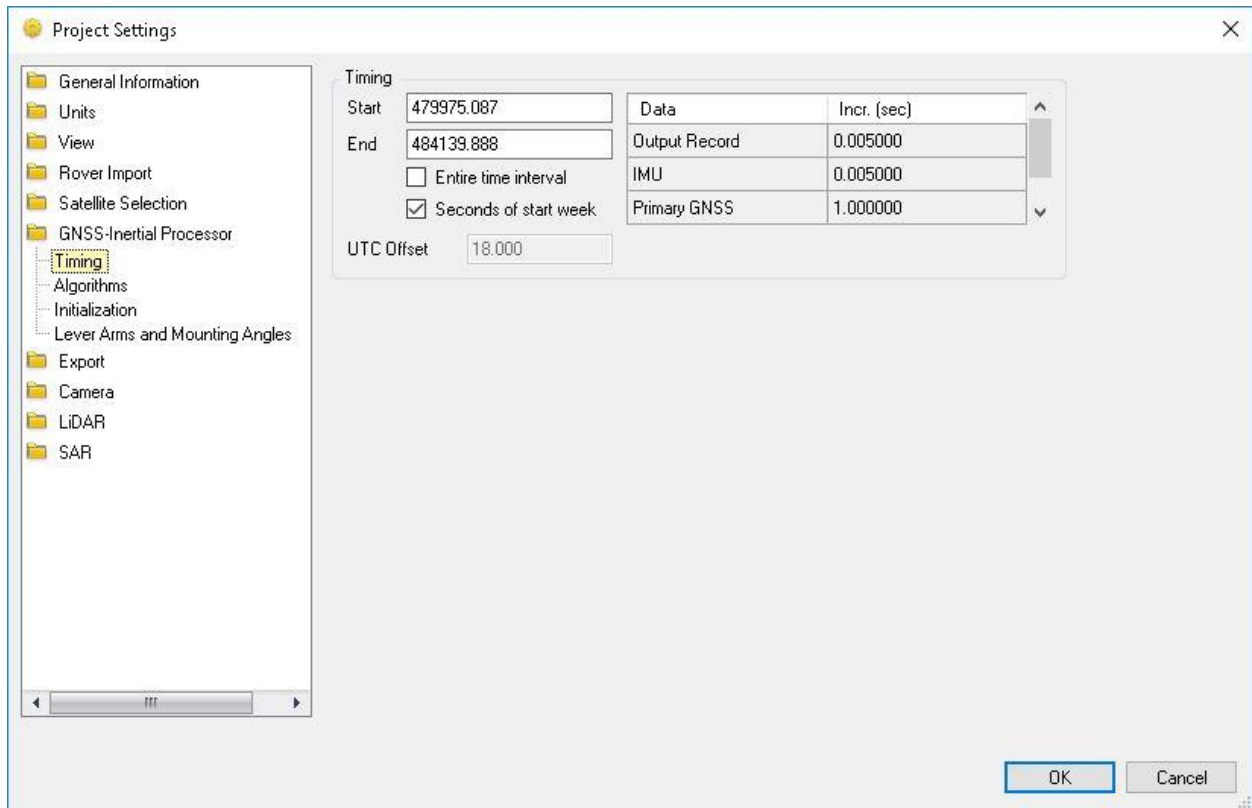
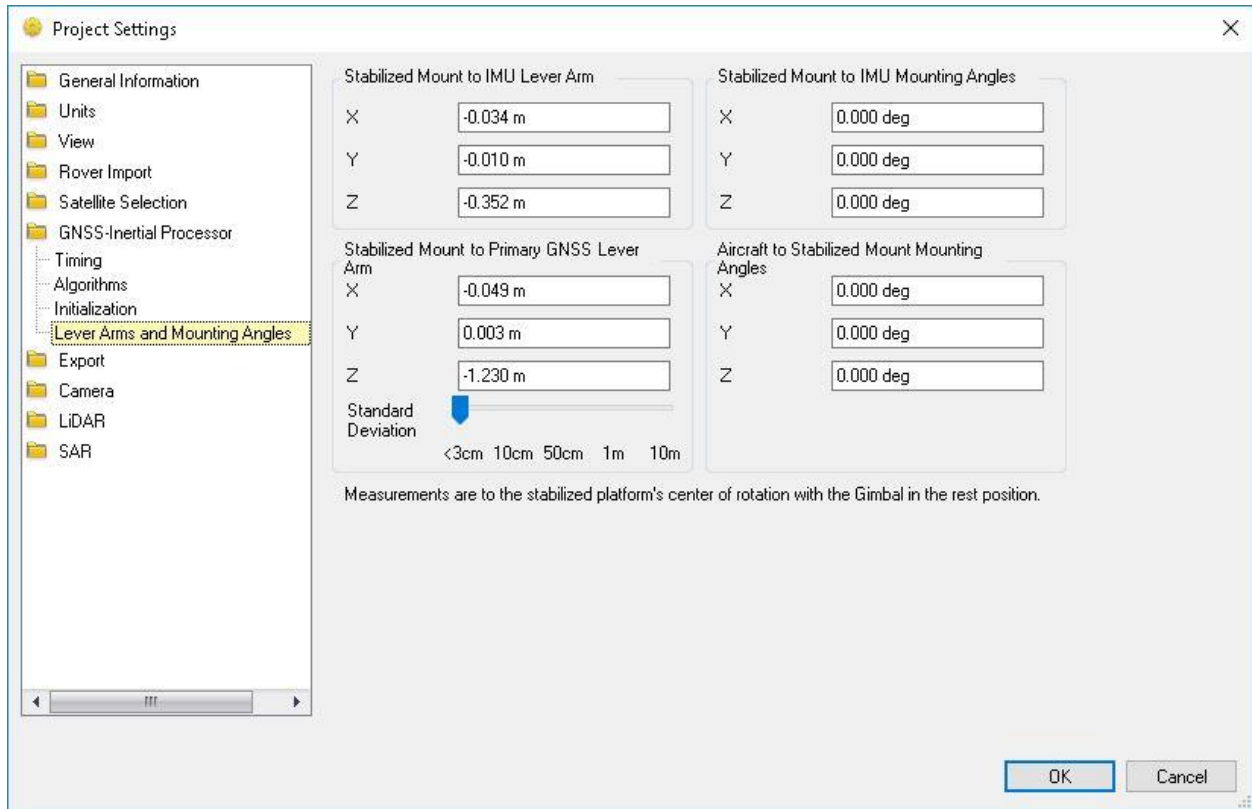


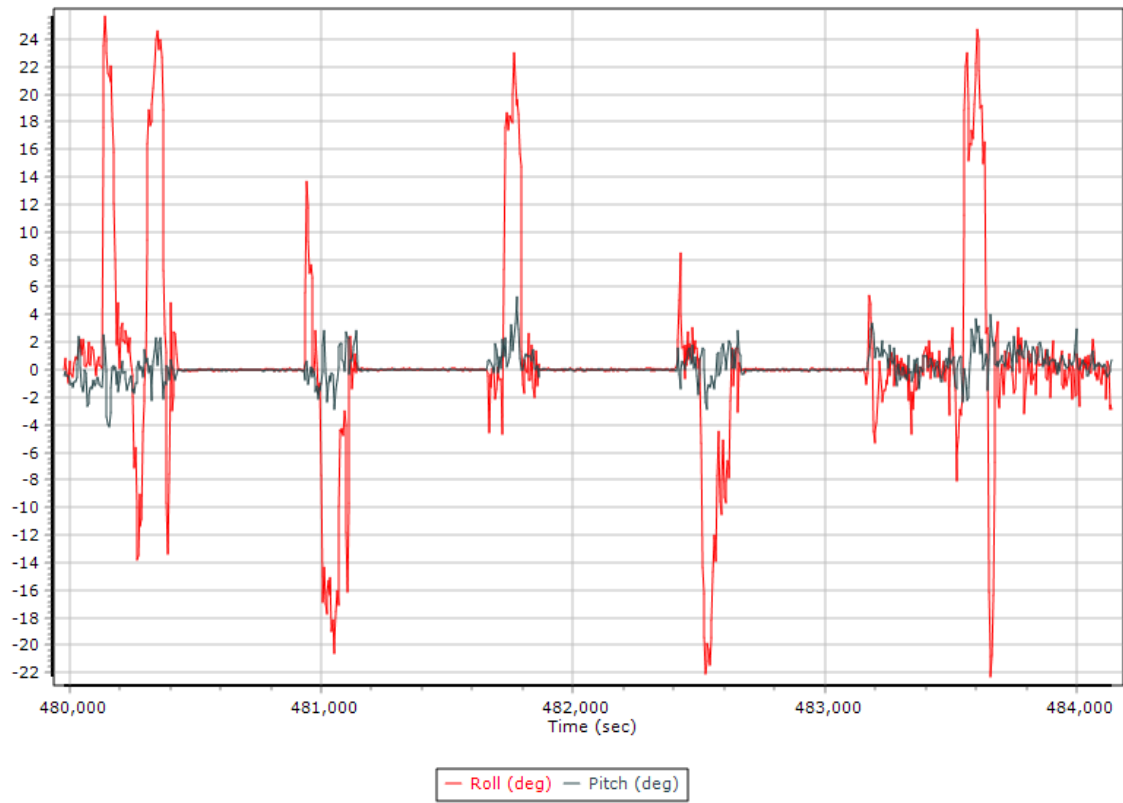
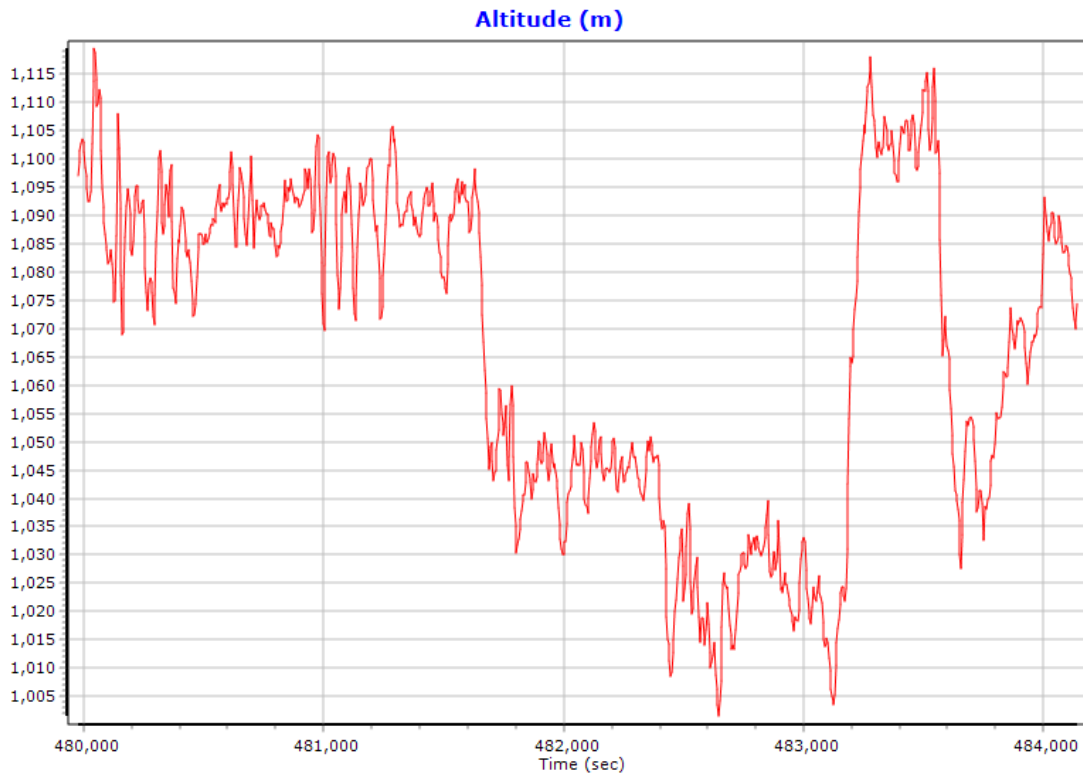
— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

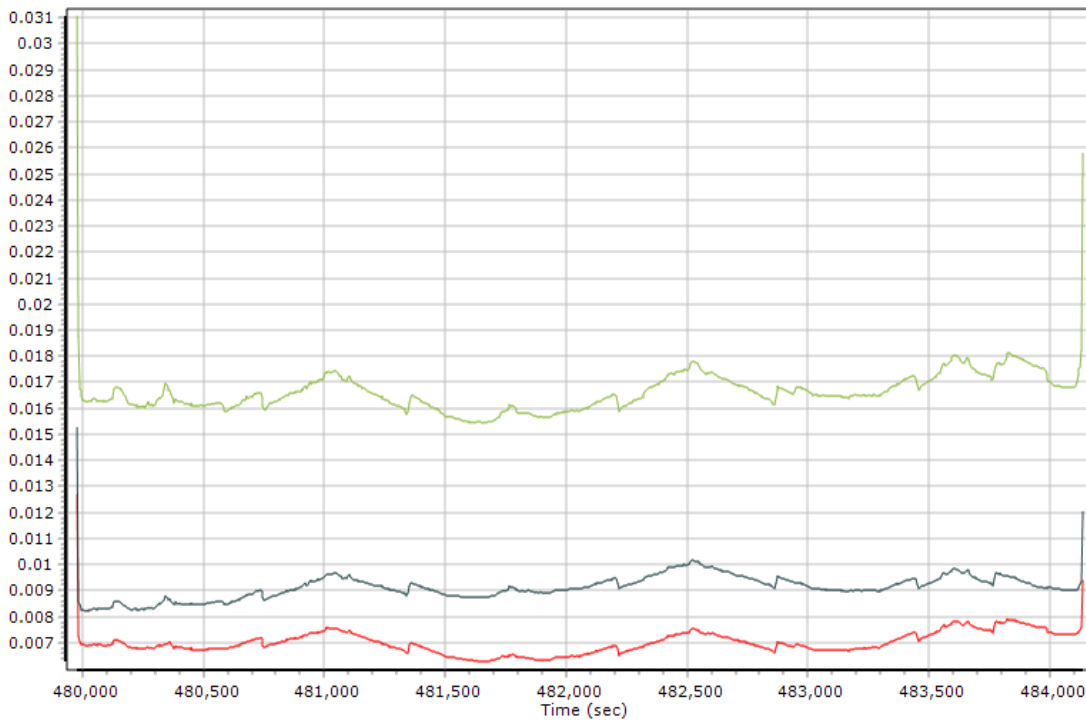


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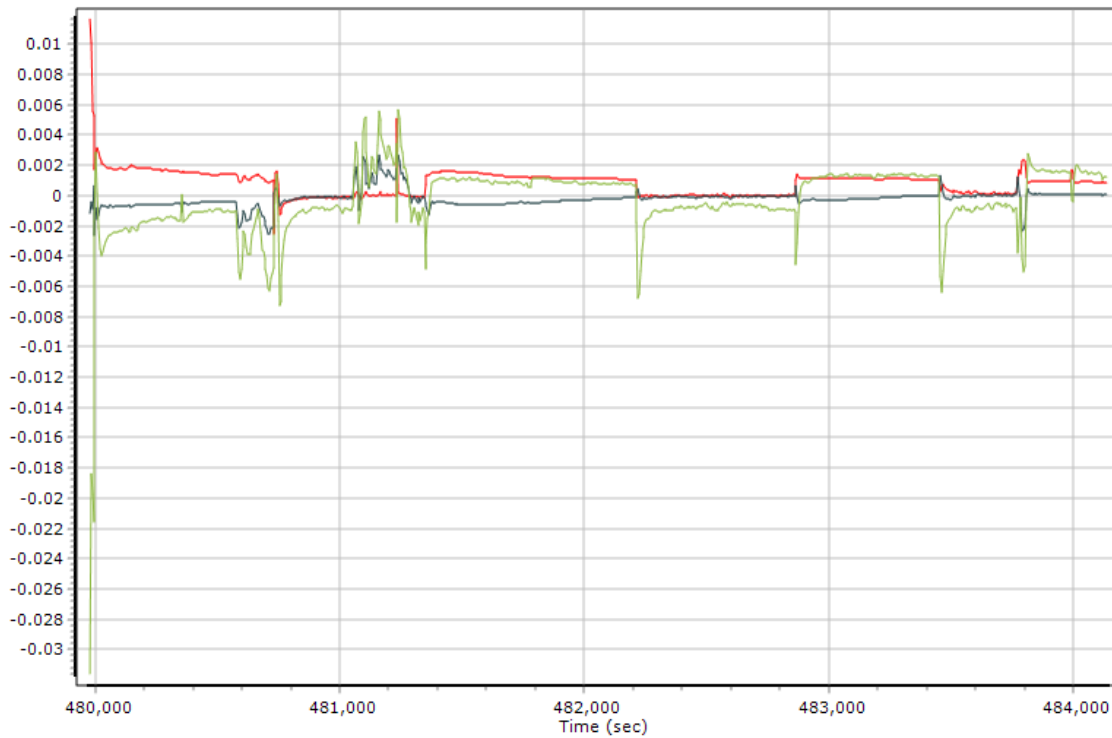




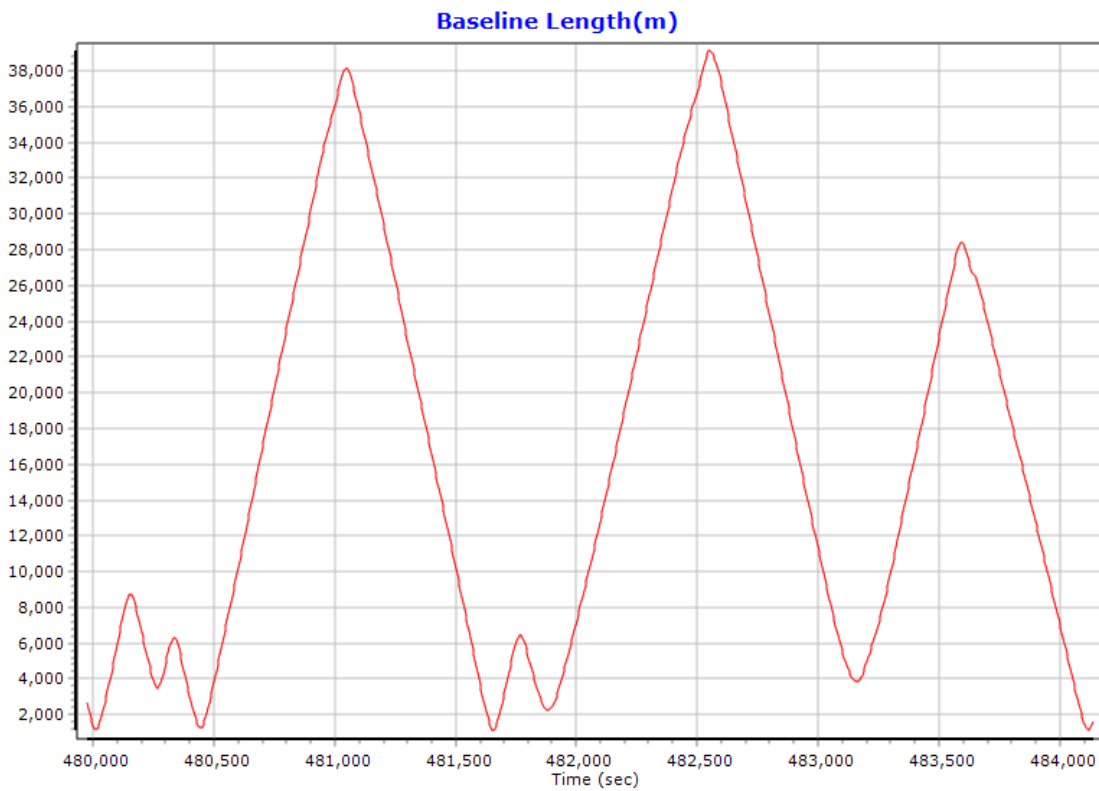
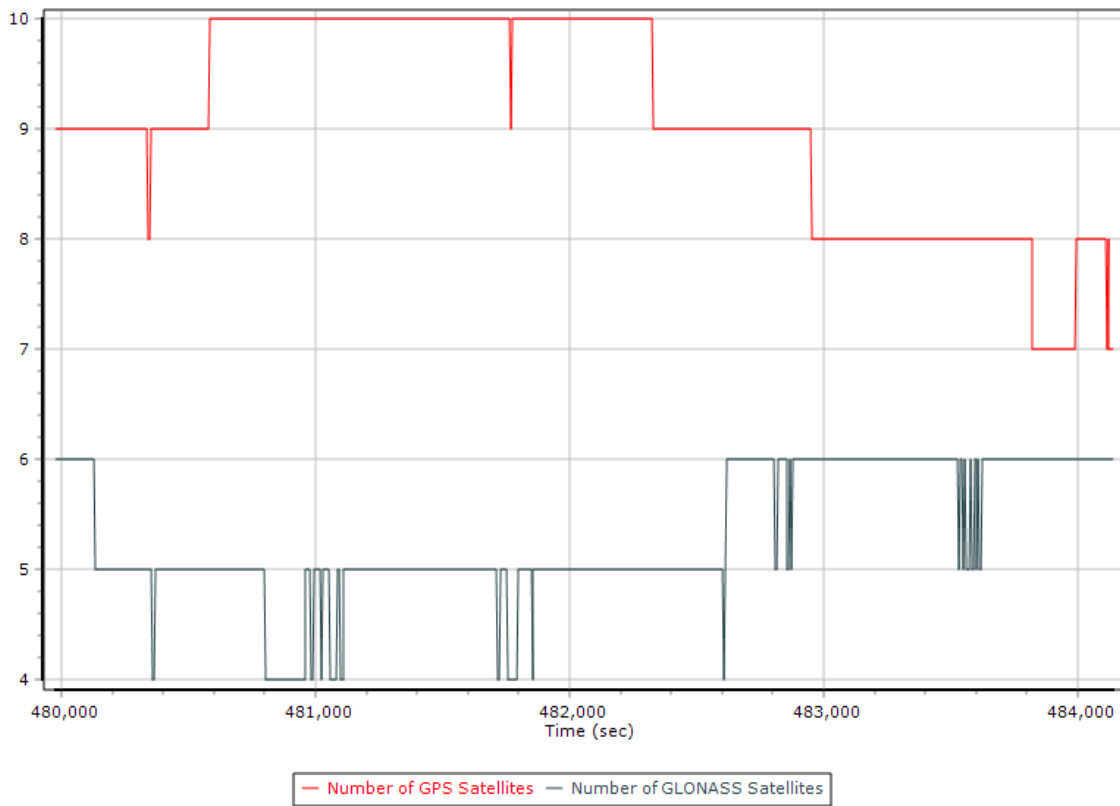




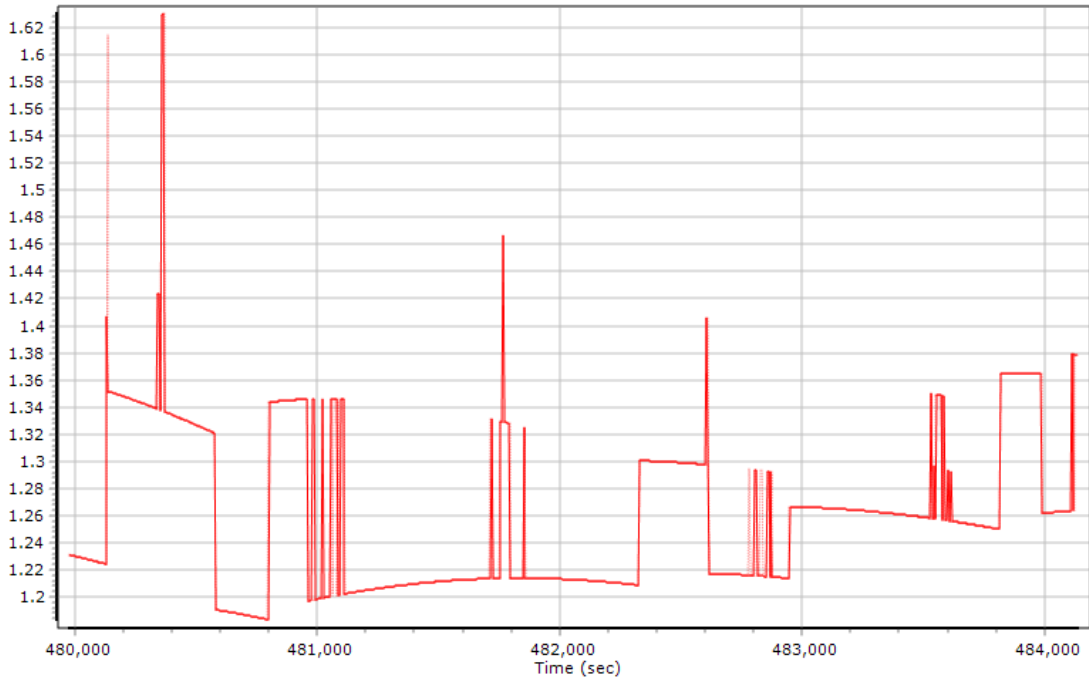
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



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

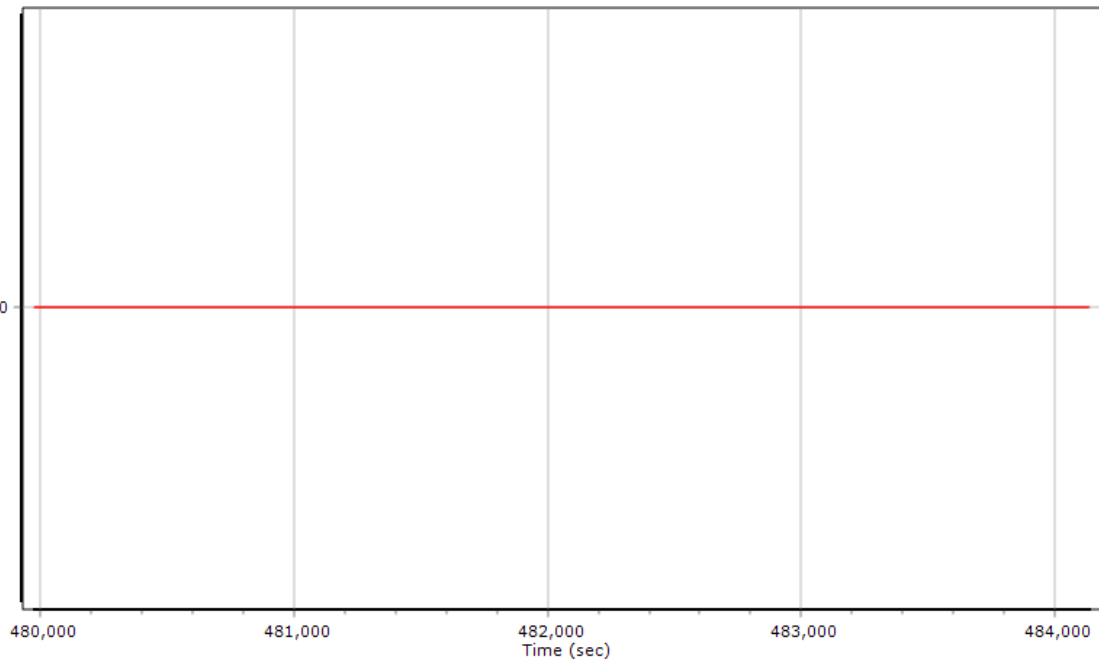


PDOP



Forward Reverse

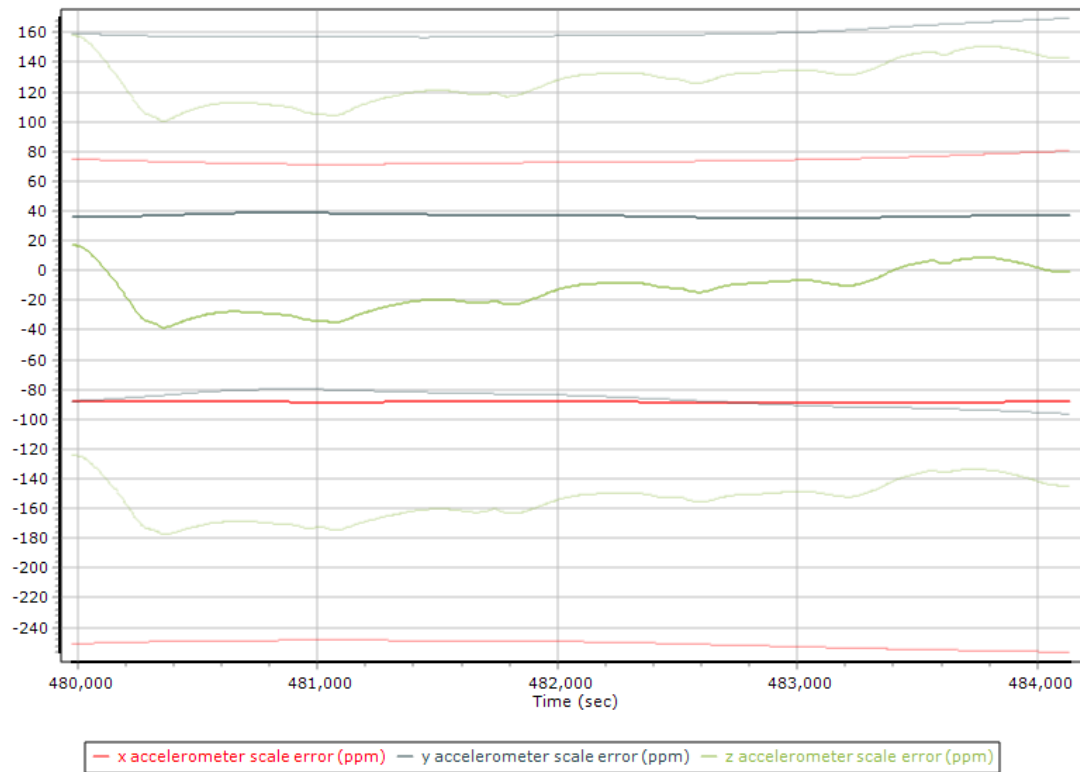
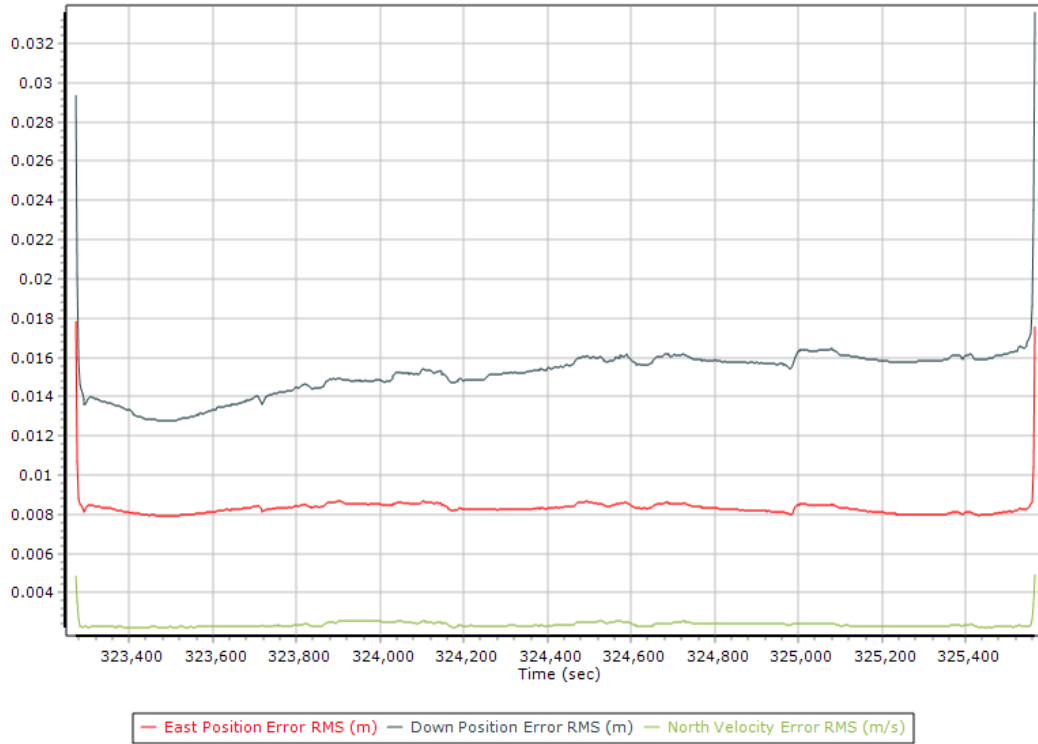
Processing Mode

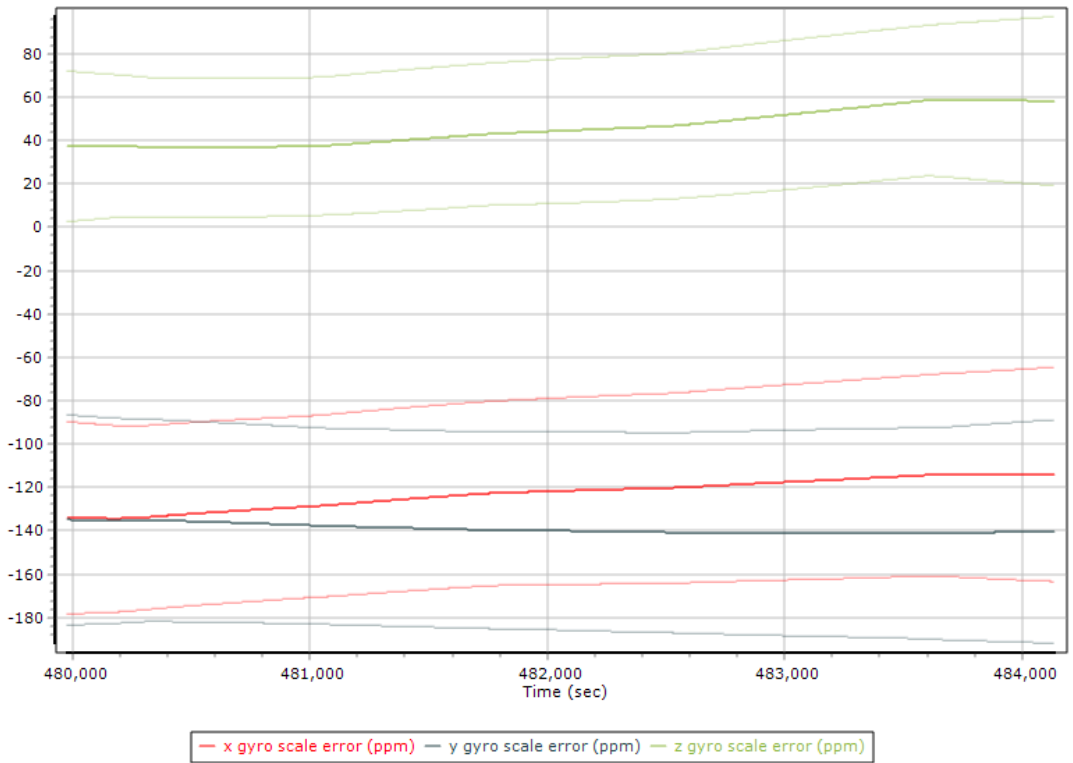
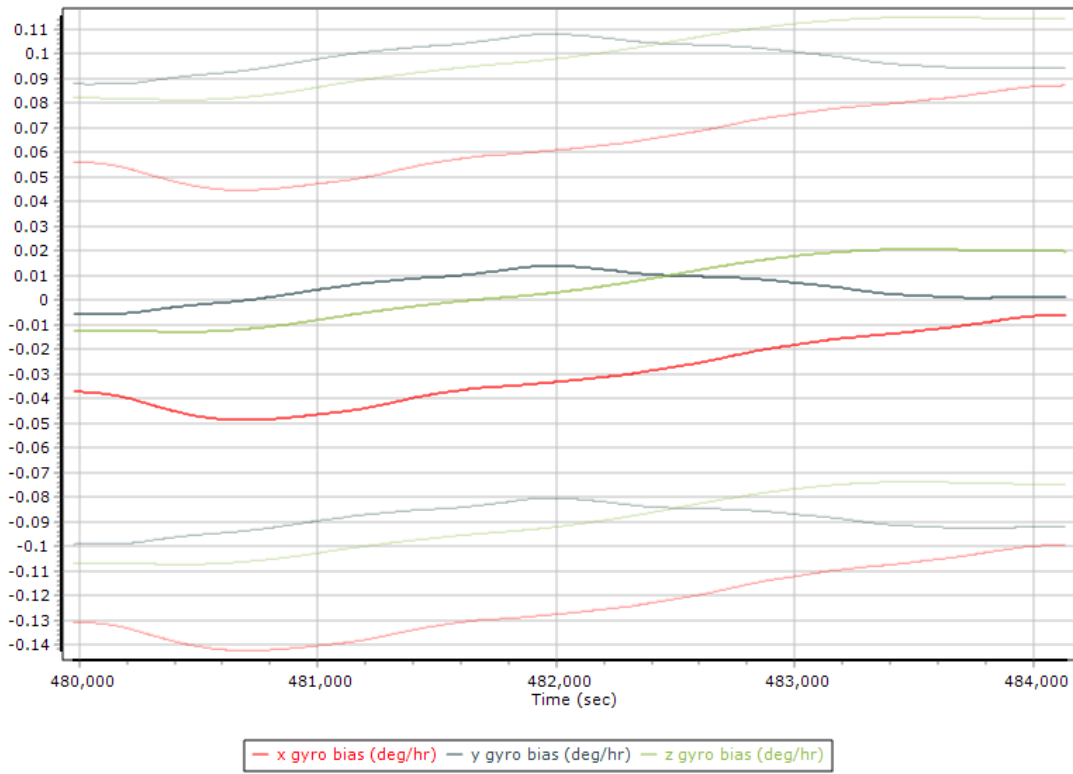


Forward Reverse

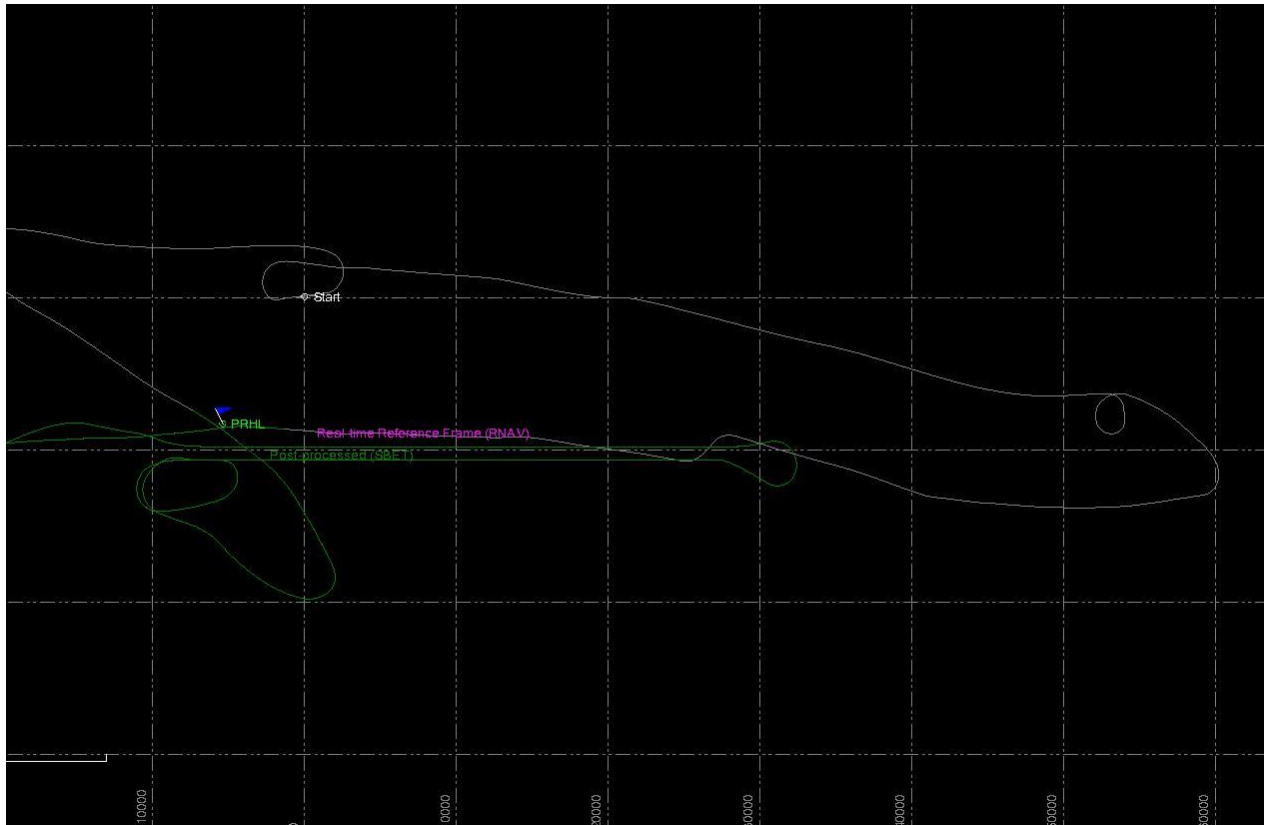
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





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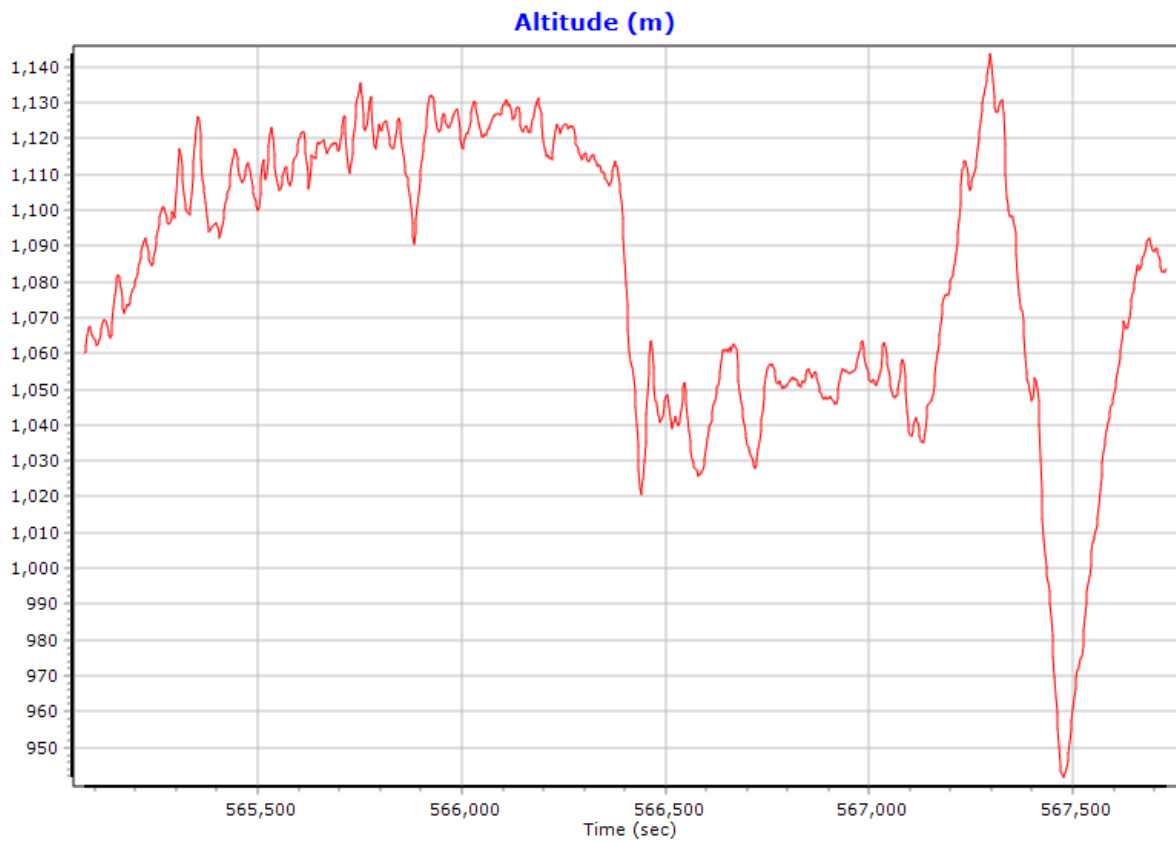
Stabilized Mount to IMU Lever Arm	Stabilized Mount to IMU Mounting Angles
X: -0.034 m	X: 0.000 deg
Y: -0.010 m	Y: 0.000 deg
Z: -0.352 m	Z: 0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	Aircraft to Stabilized Mount Mounting Angles
X: -0.049 m	X: 0.000 deg
Y: 0.003 m	Y: 0.000 deg
Z: -1.230 m	Z: 0.000 deg
Standard Deviation: <3cm 10cm 50cm 1m 10m	

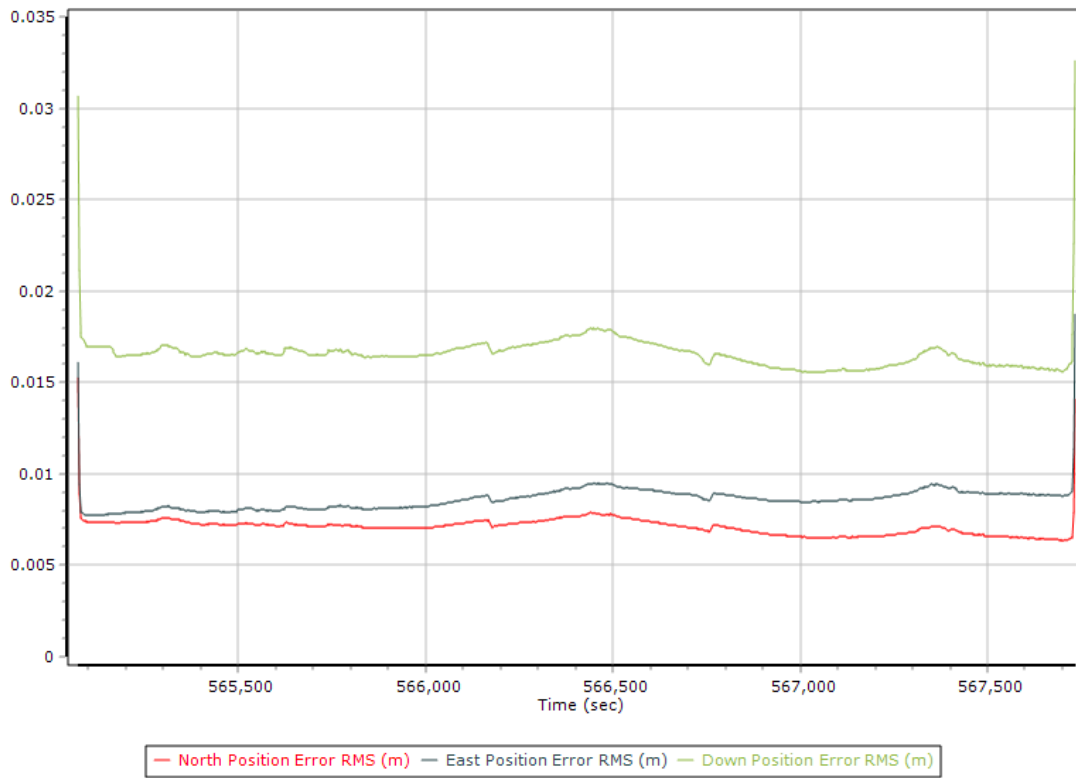
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

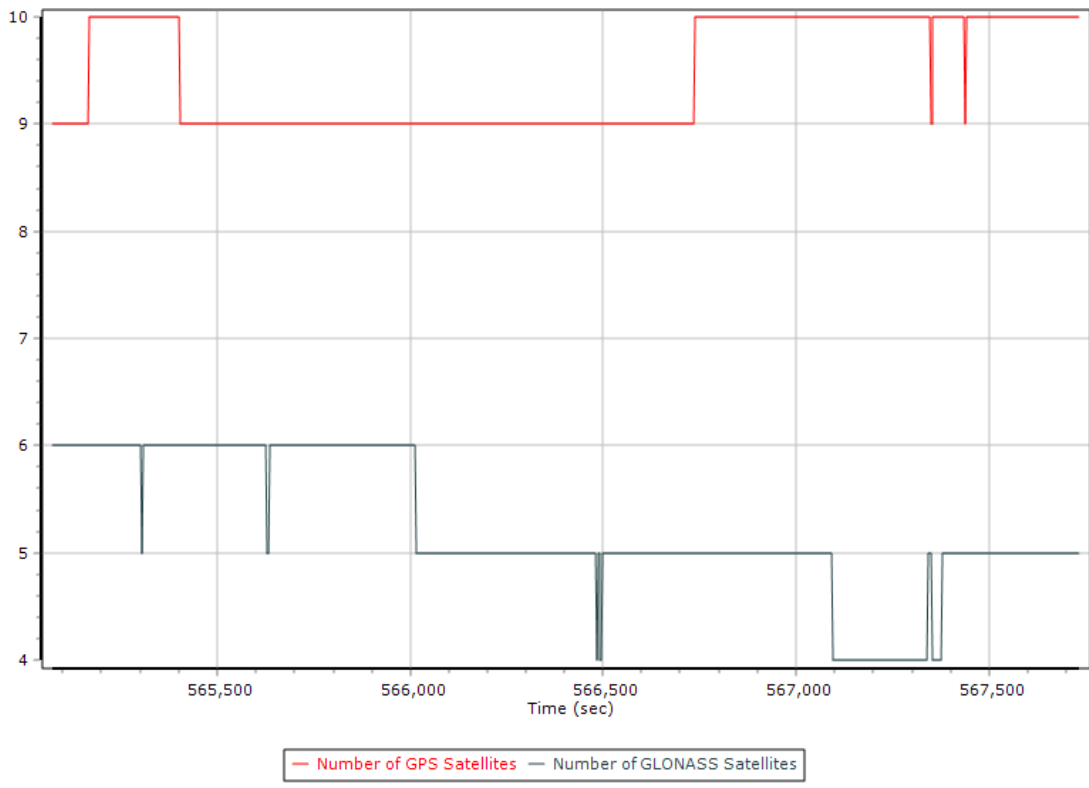
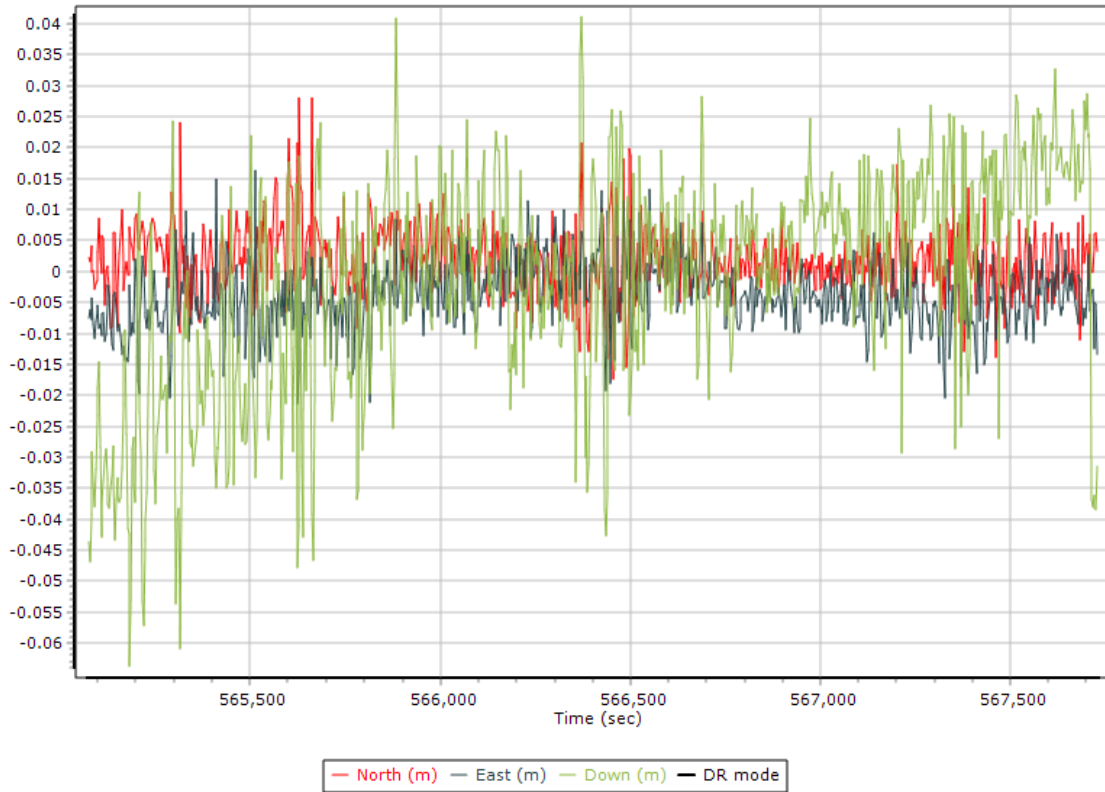
Timing

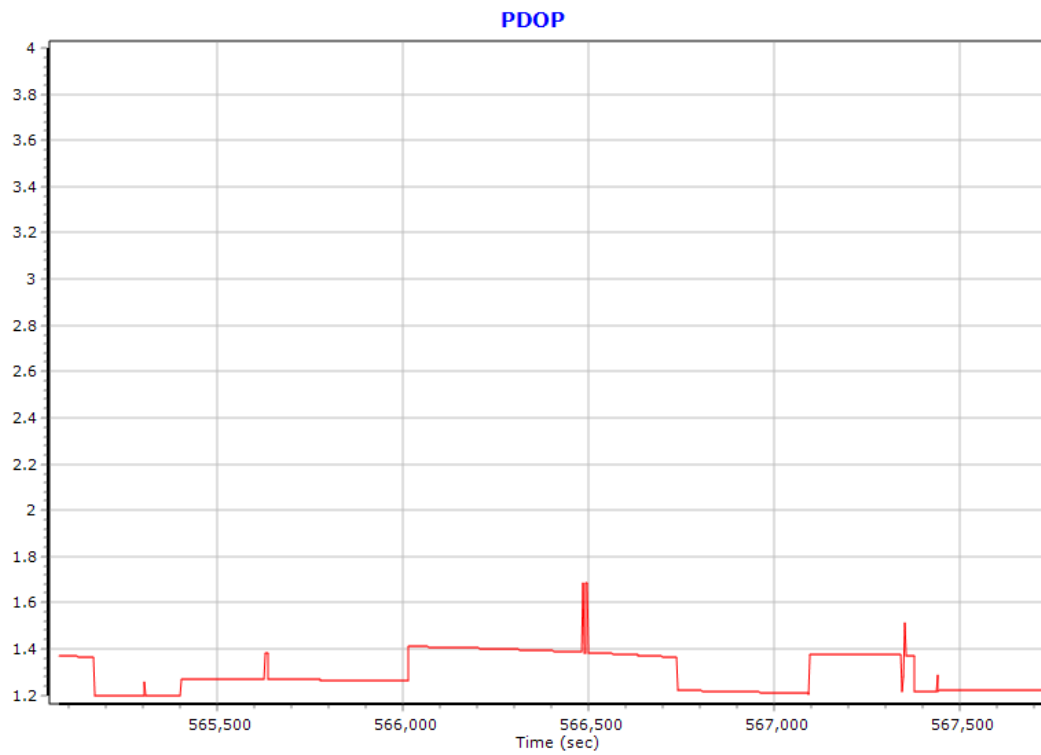
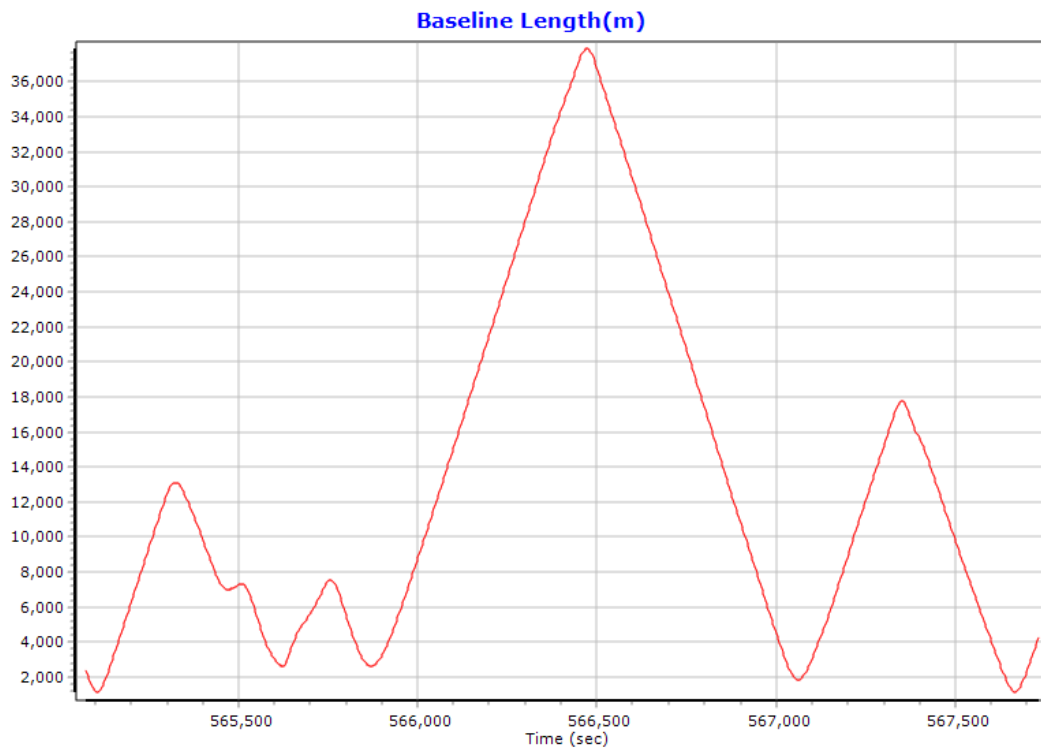
Start	565072.736	Data	Incr. (sec)
End	567732.446	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset

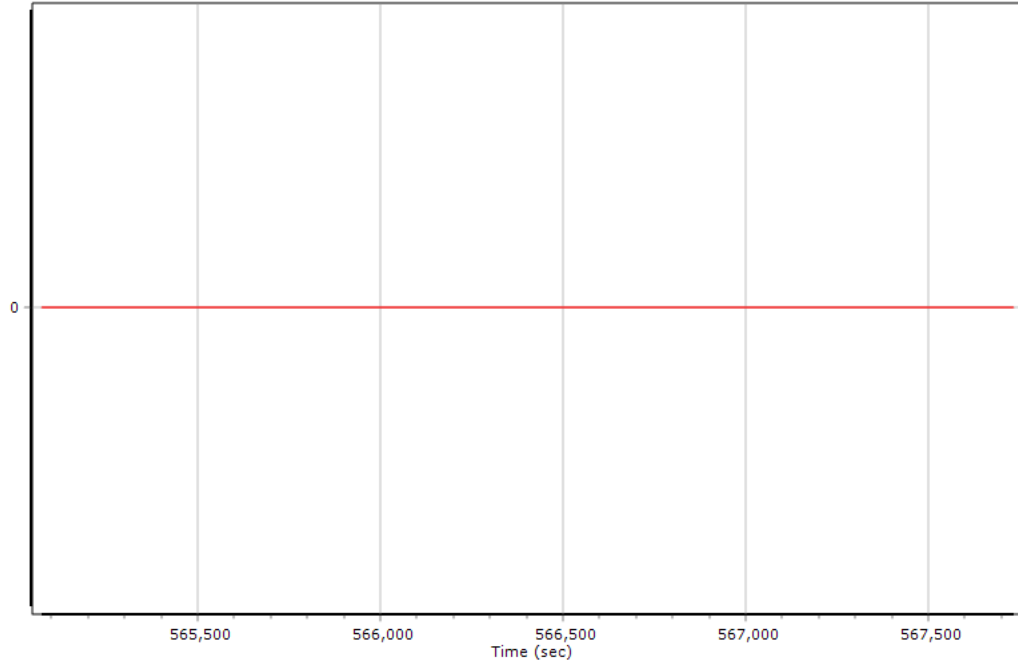






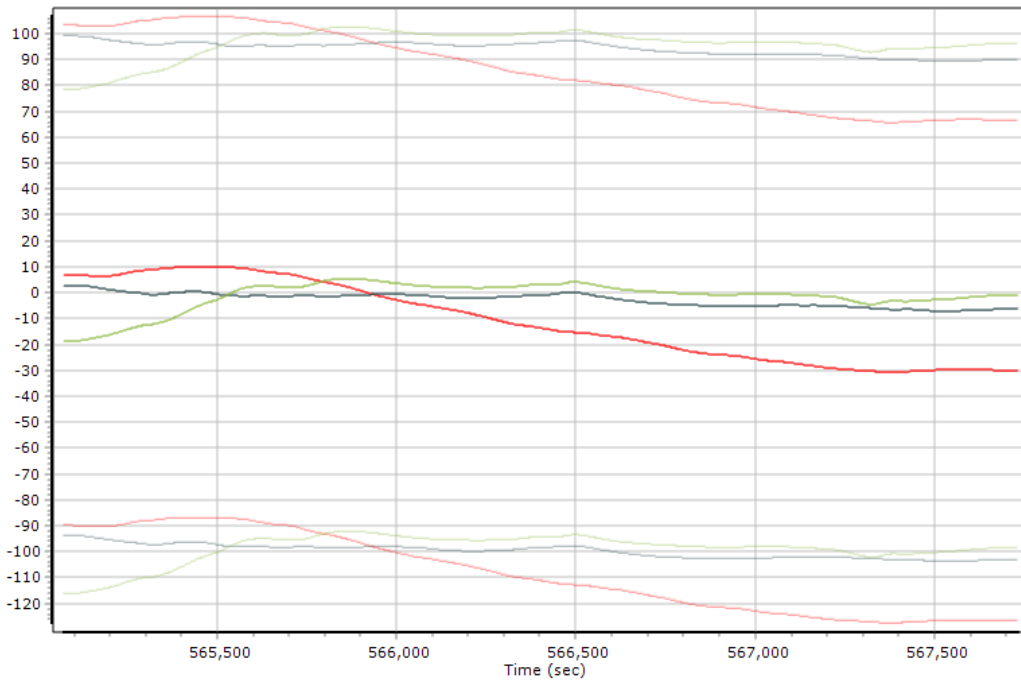


Processing Mode

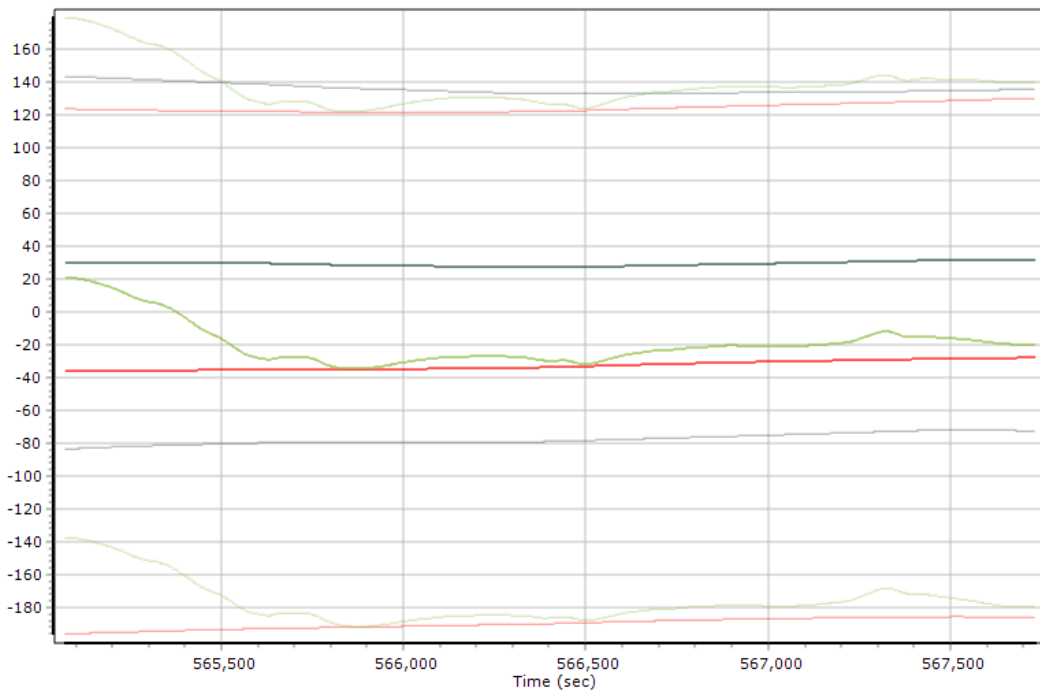


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

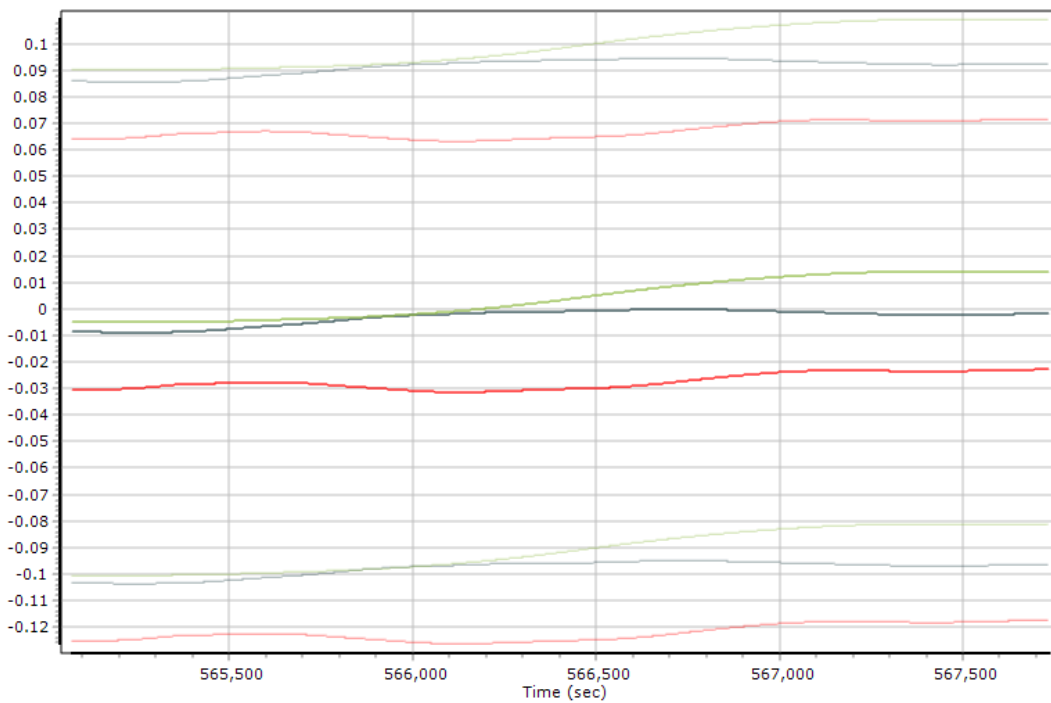
Sensor Errors



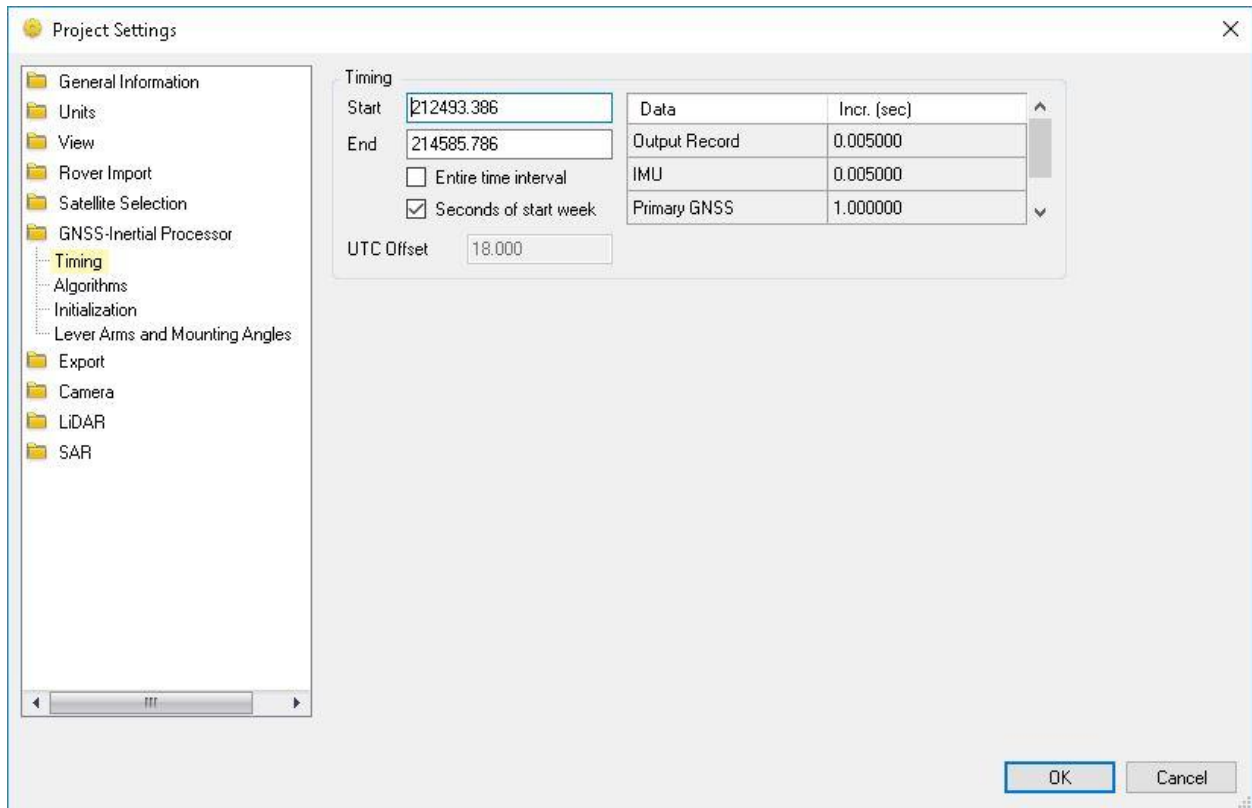
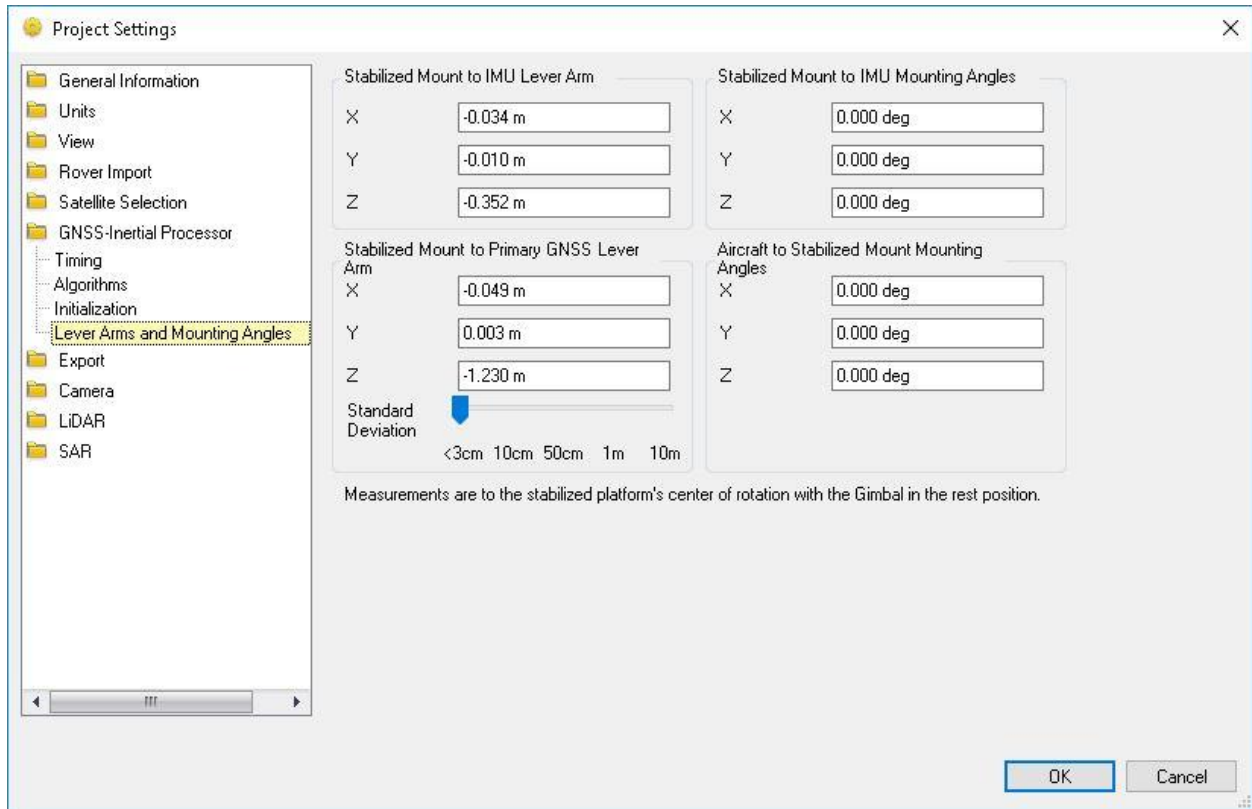
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)

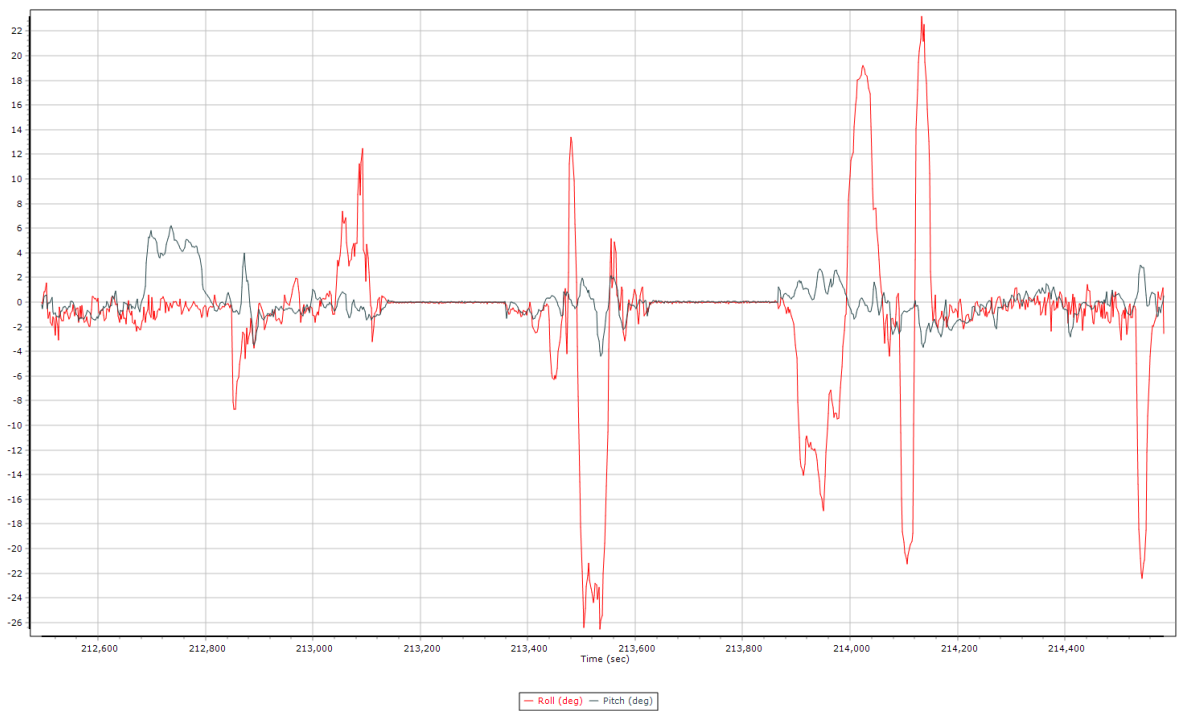
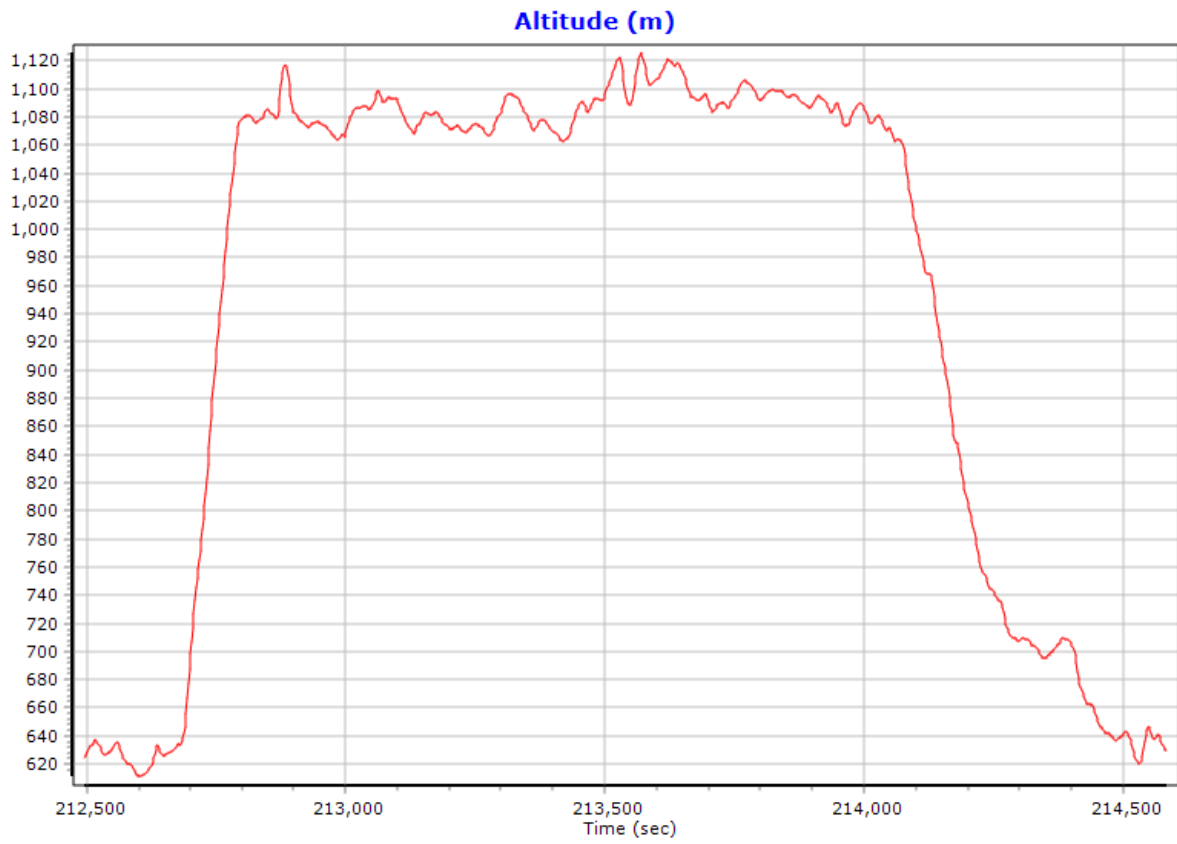


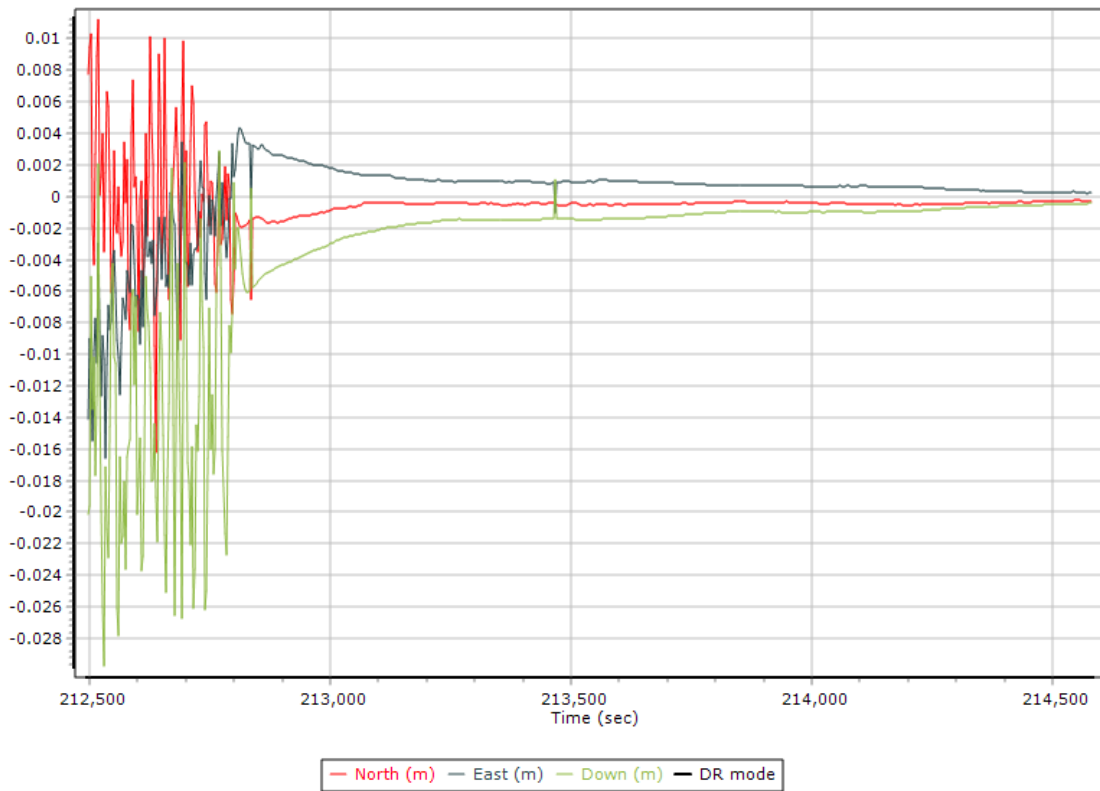
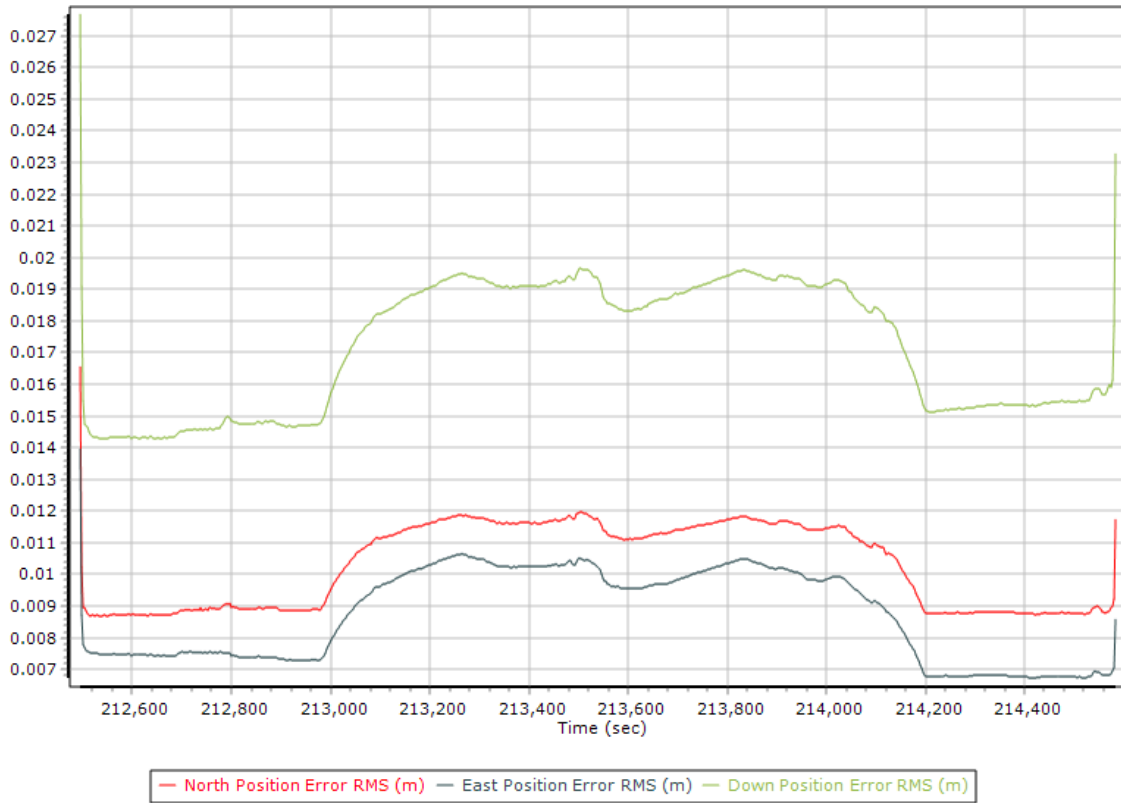
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

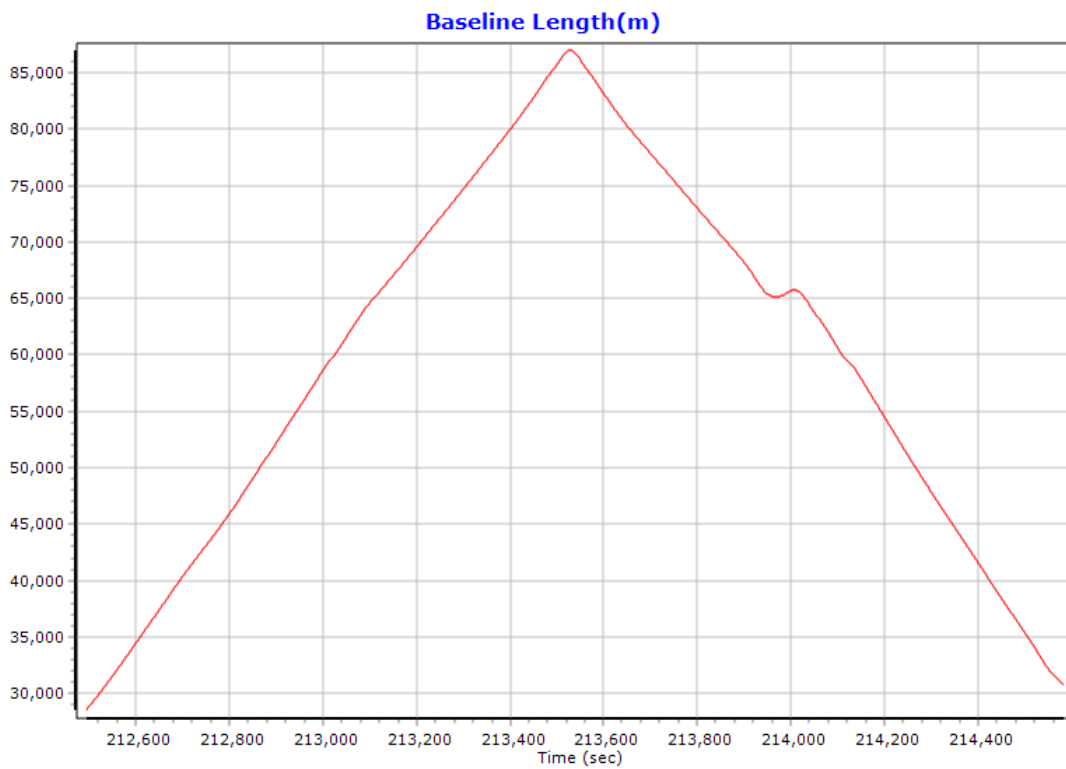
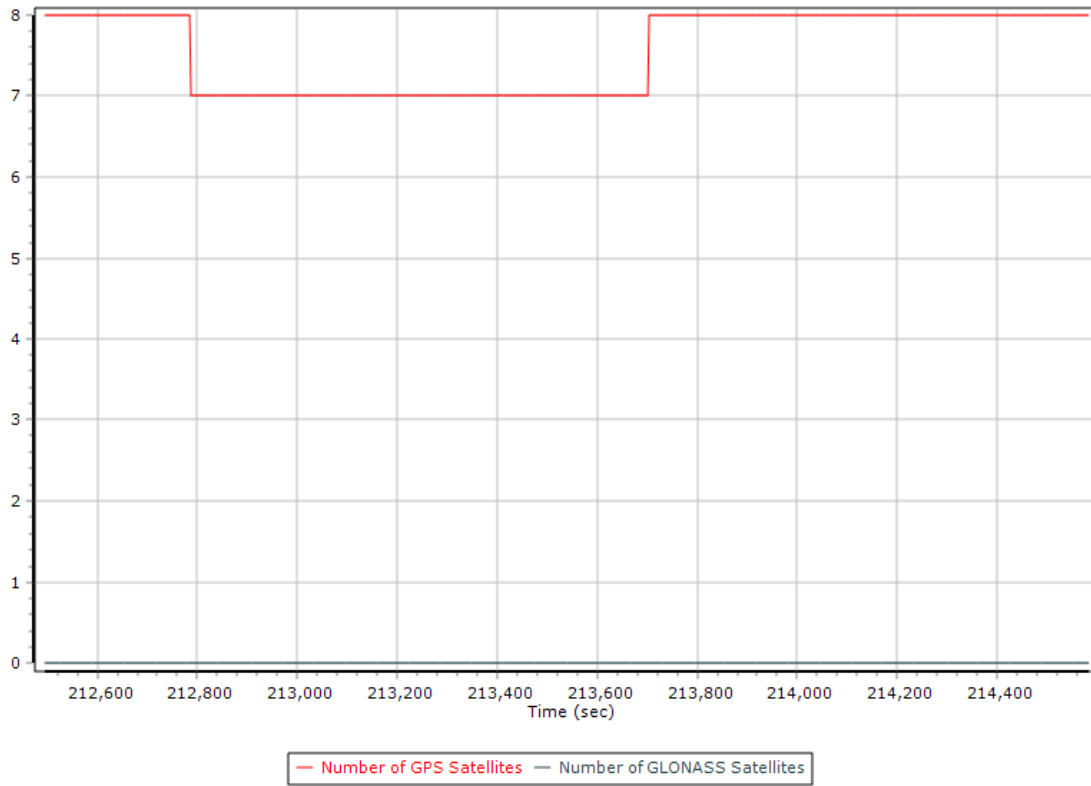


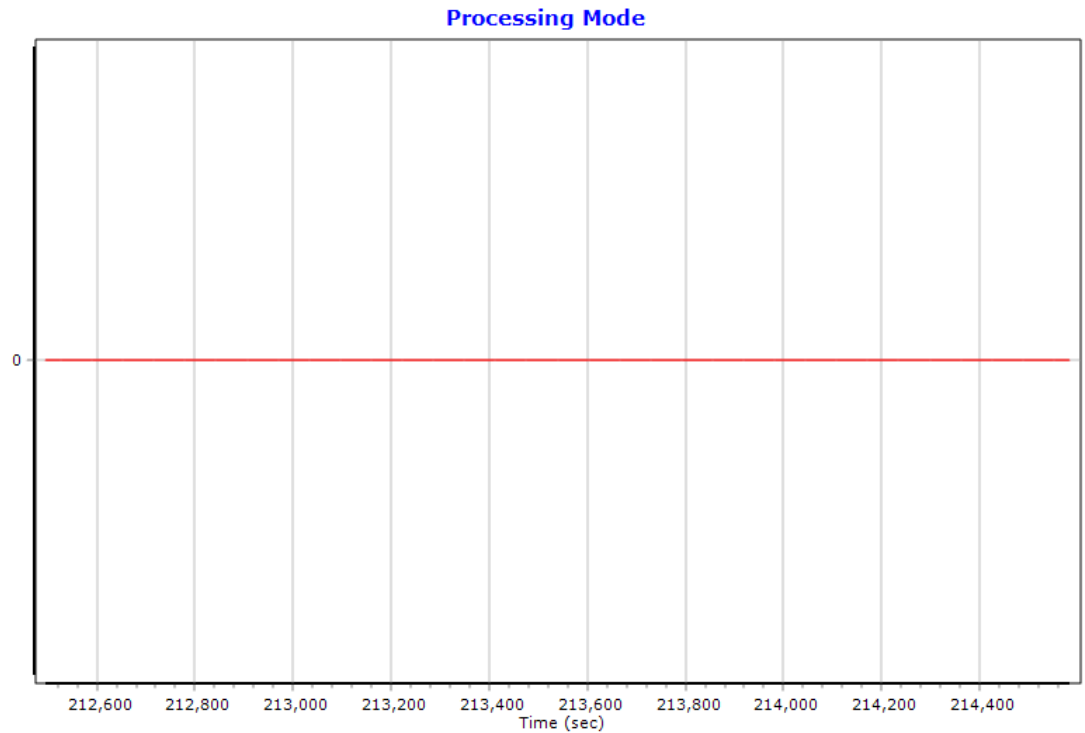
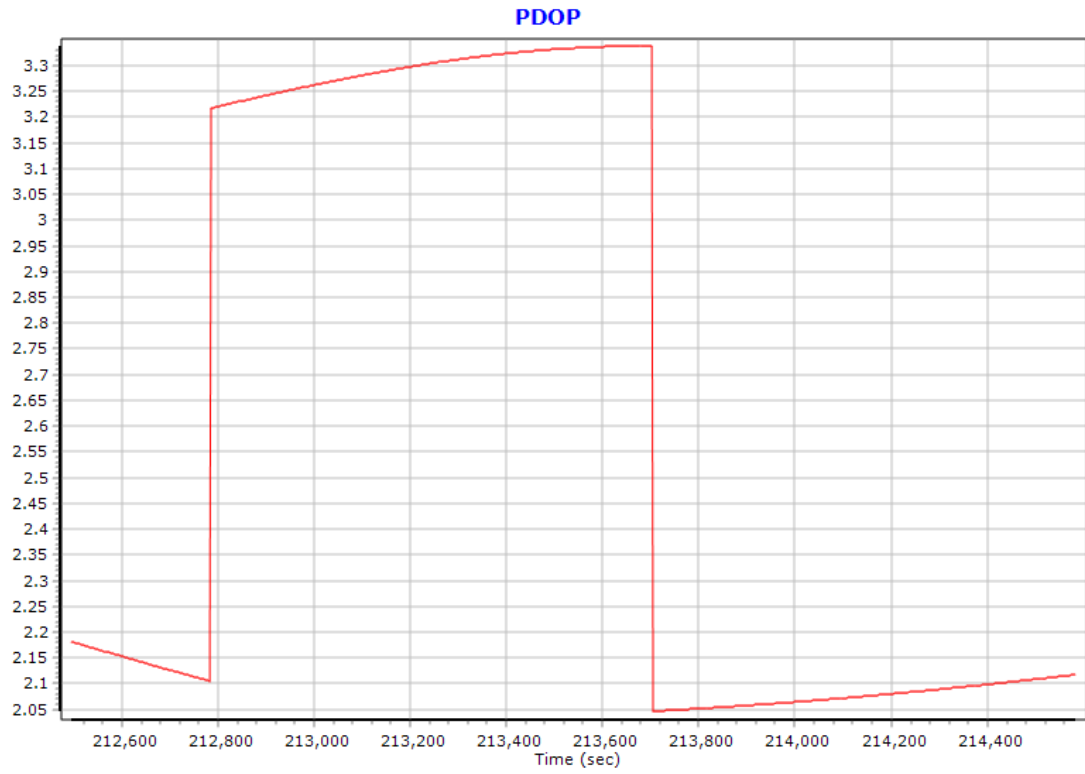
— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)





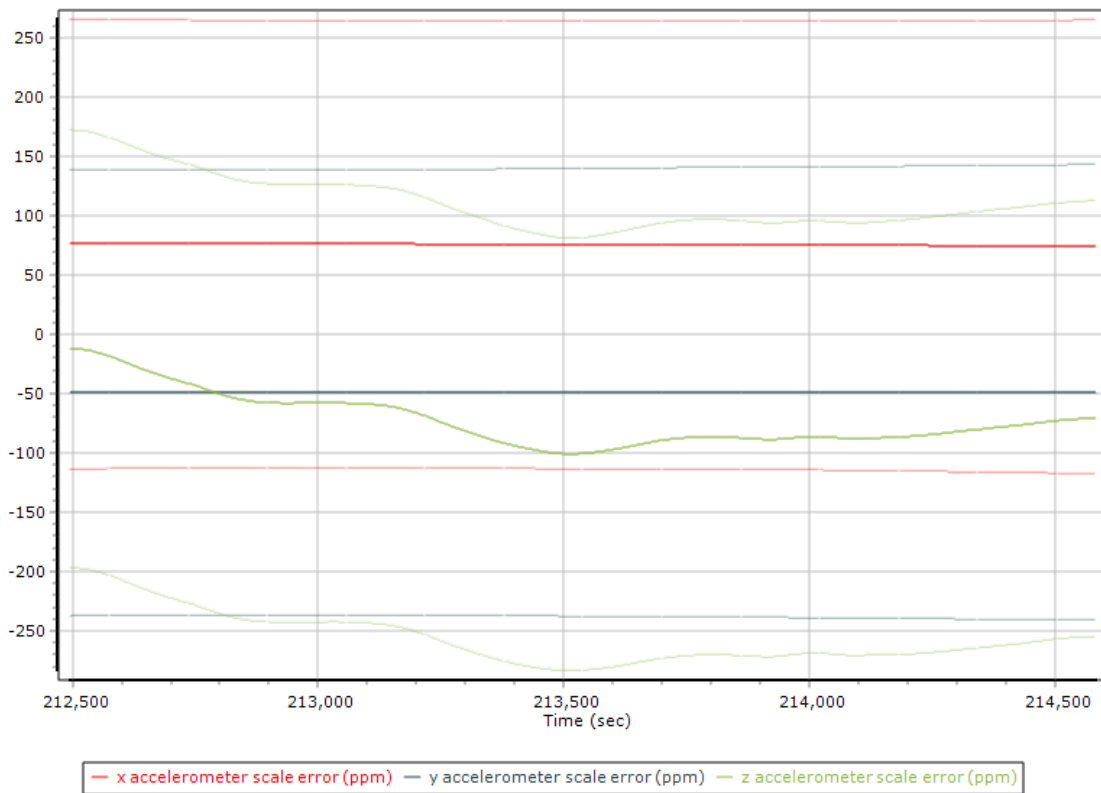
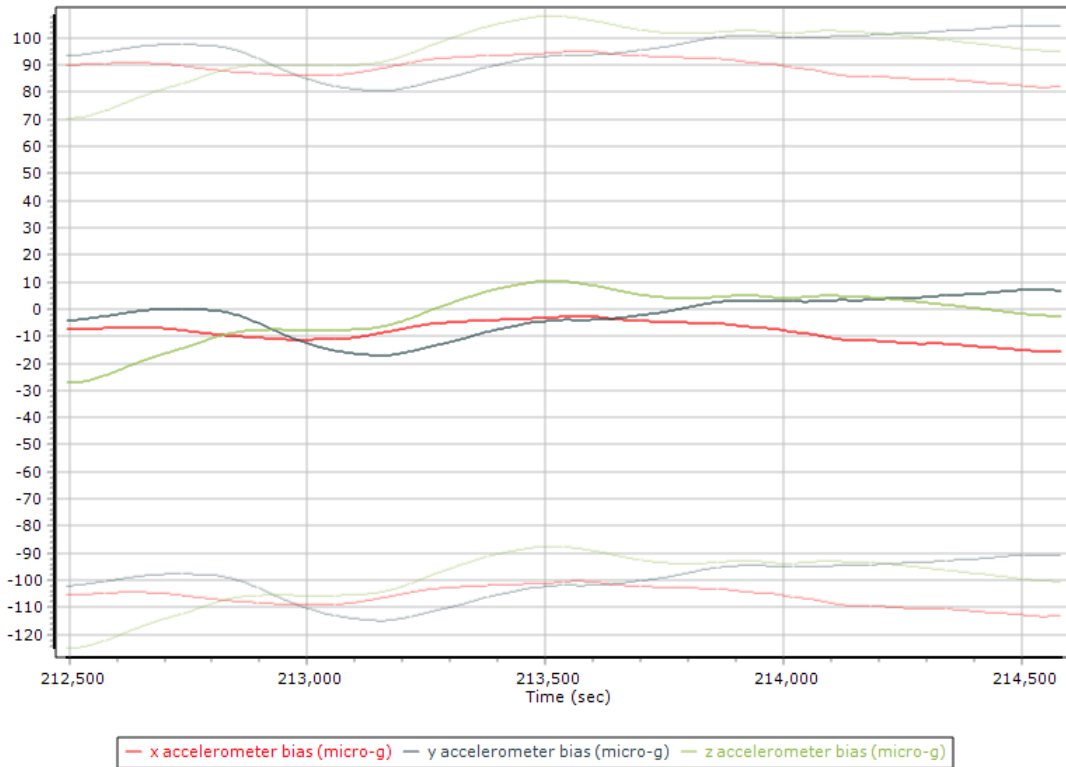


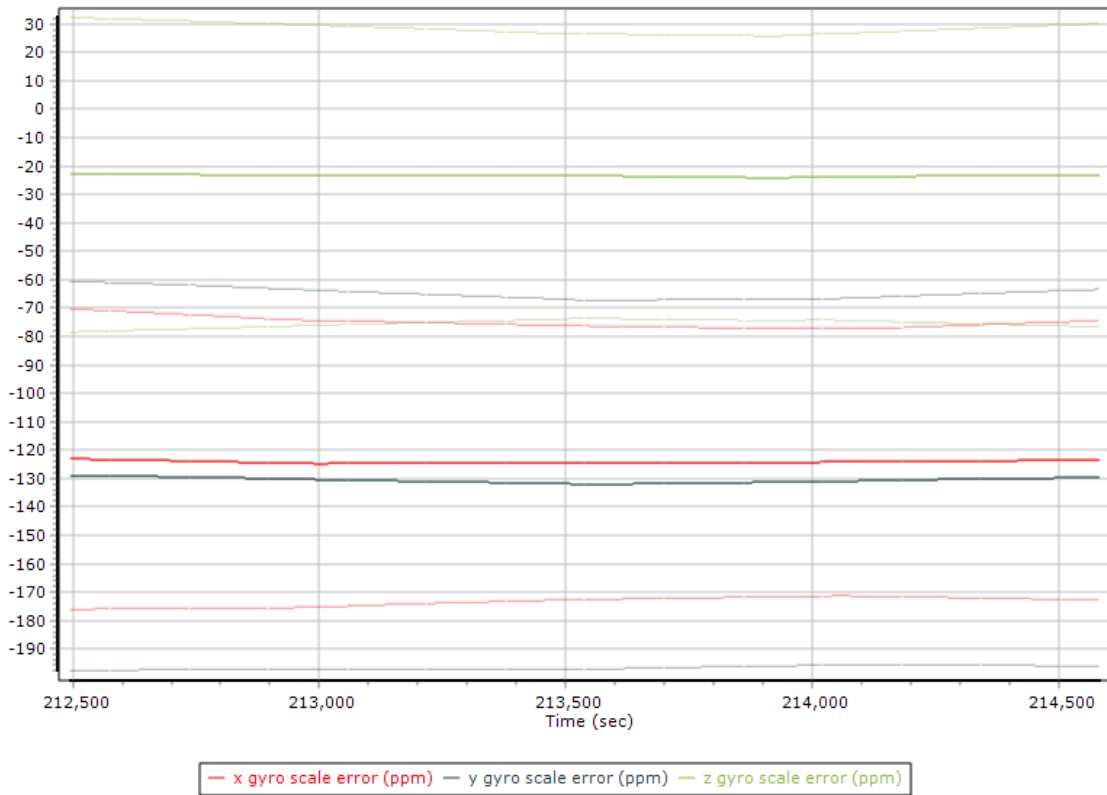
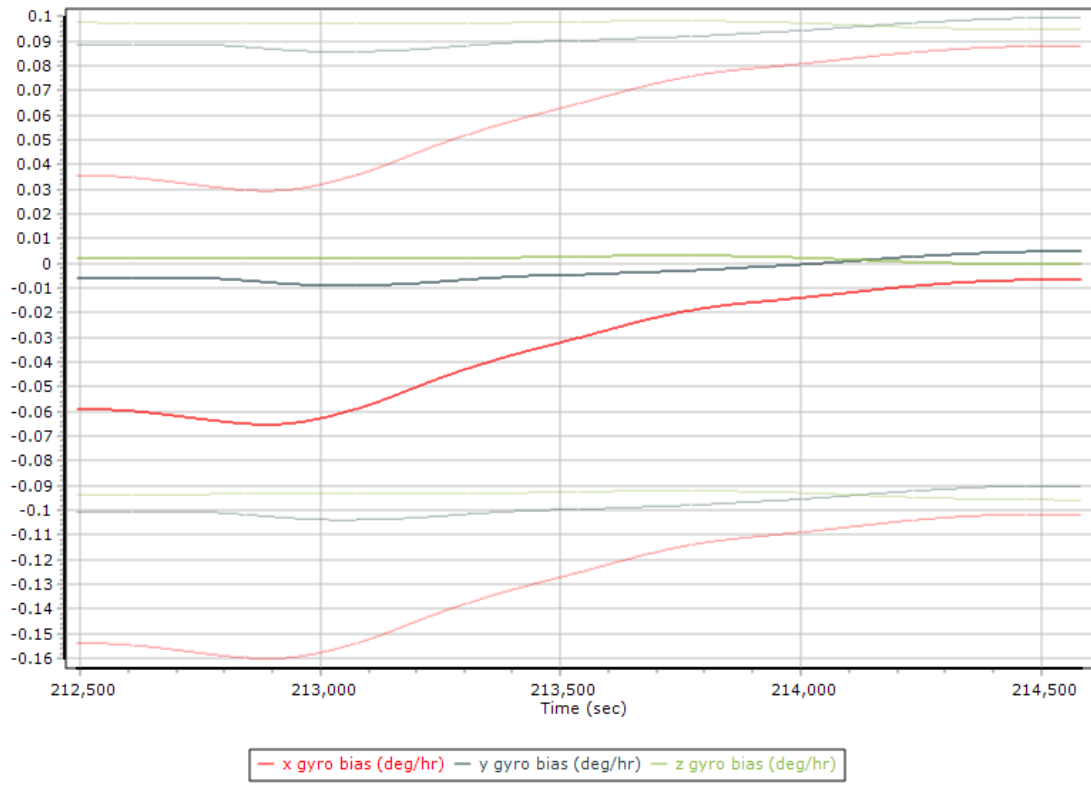




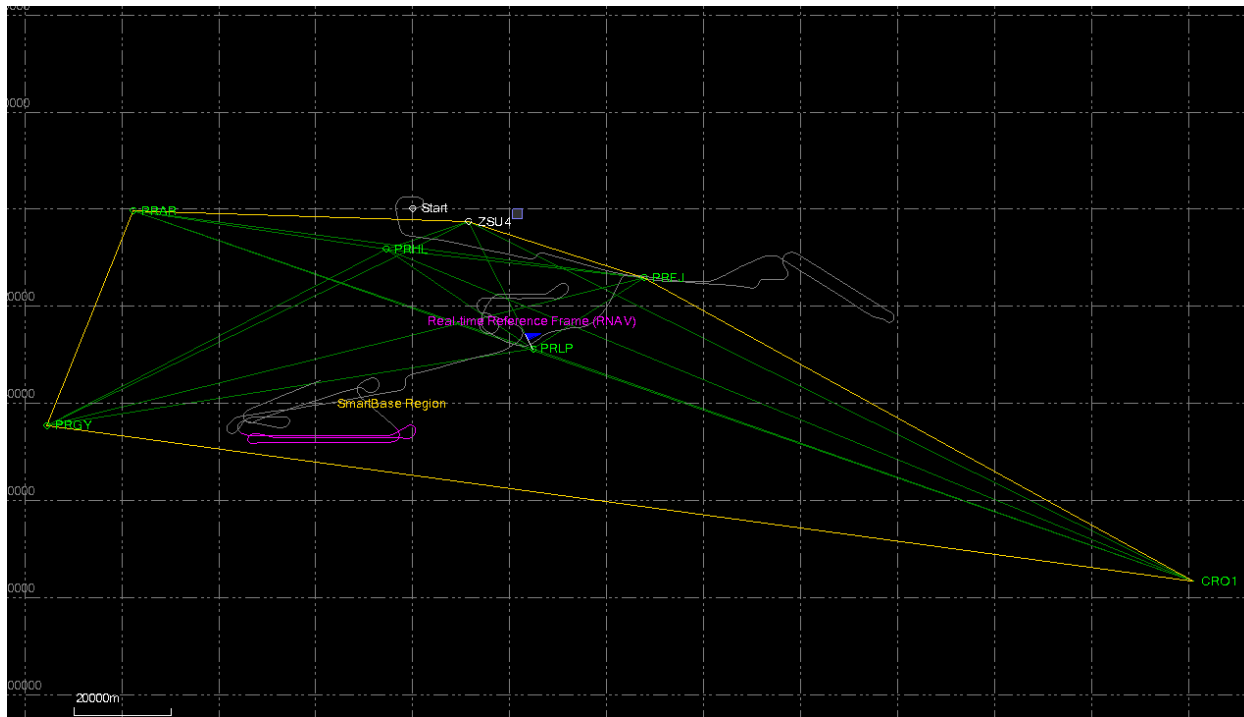
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





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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

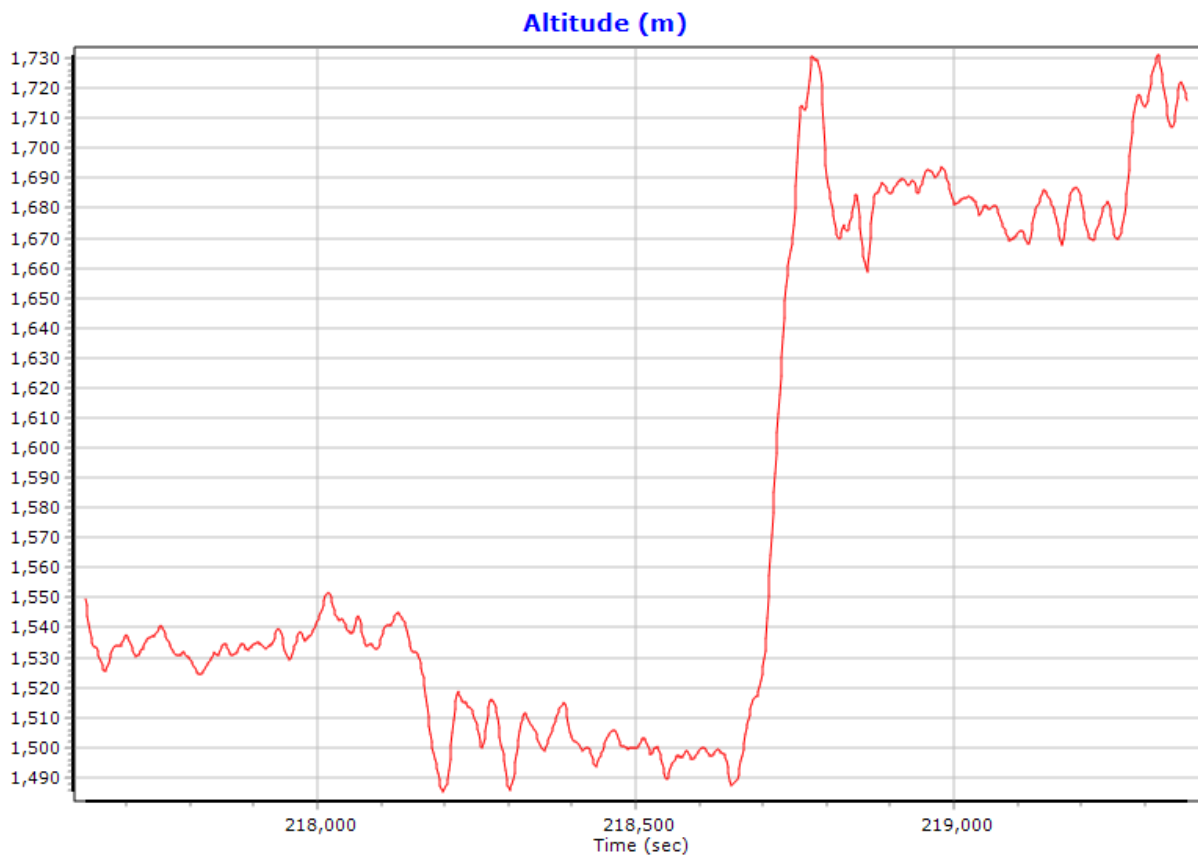
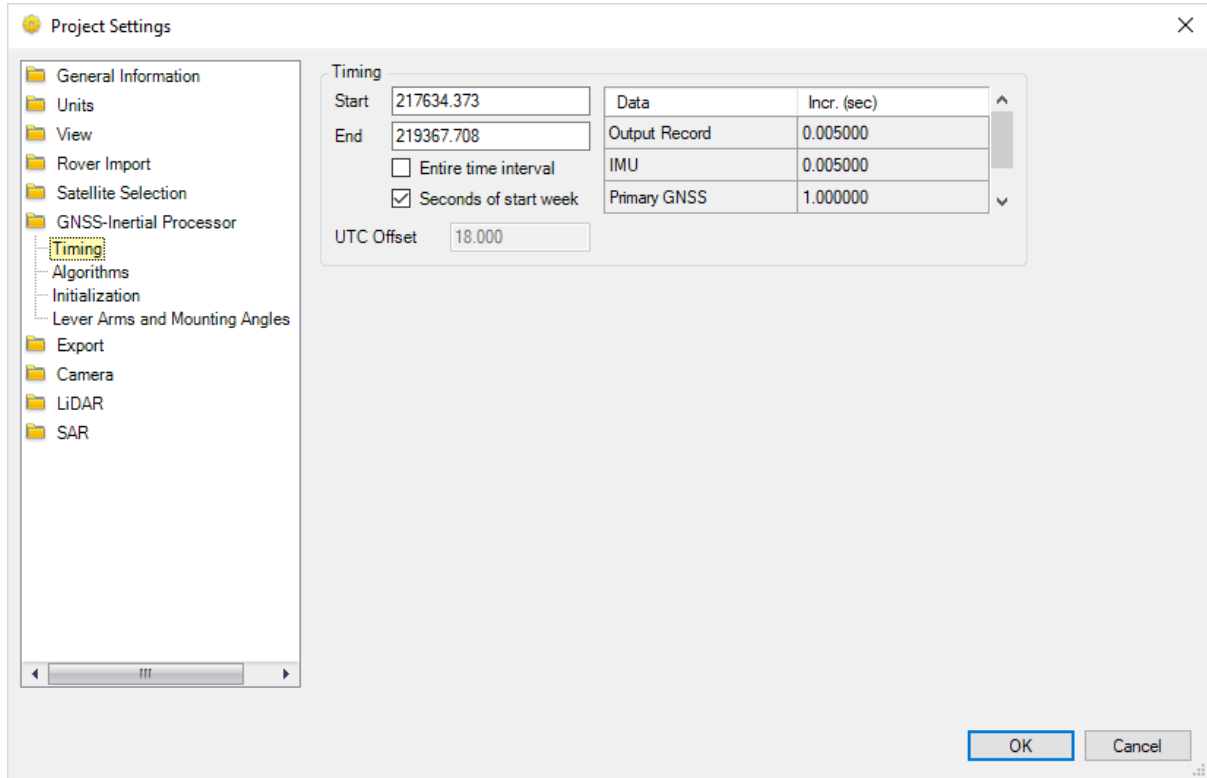
Stabilized Mount to IMU Lever Arm	Stabilized Mount to IMU Mounting Angles
X: -0.034 m	X: 0.000 deg
Y: -0.010 m	Y: 0.000 deg
Z: -0.352 m	Z: 0.000 deg

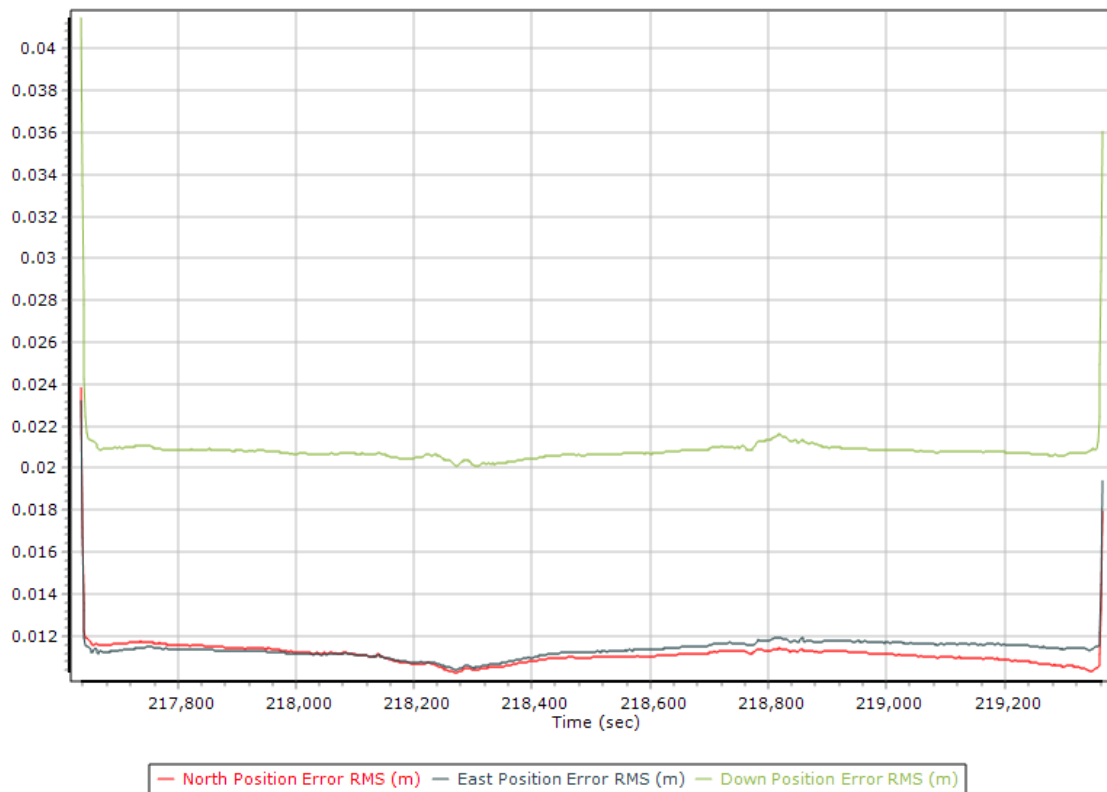
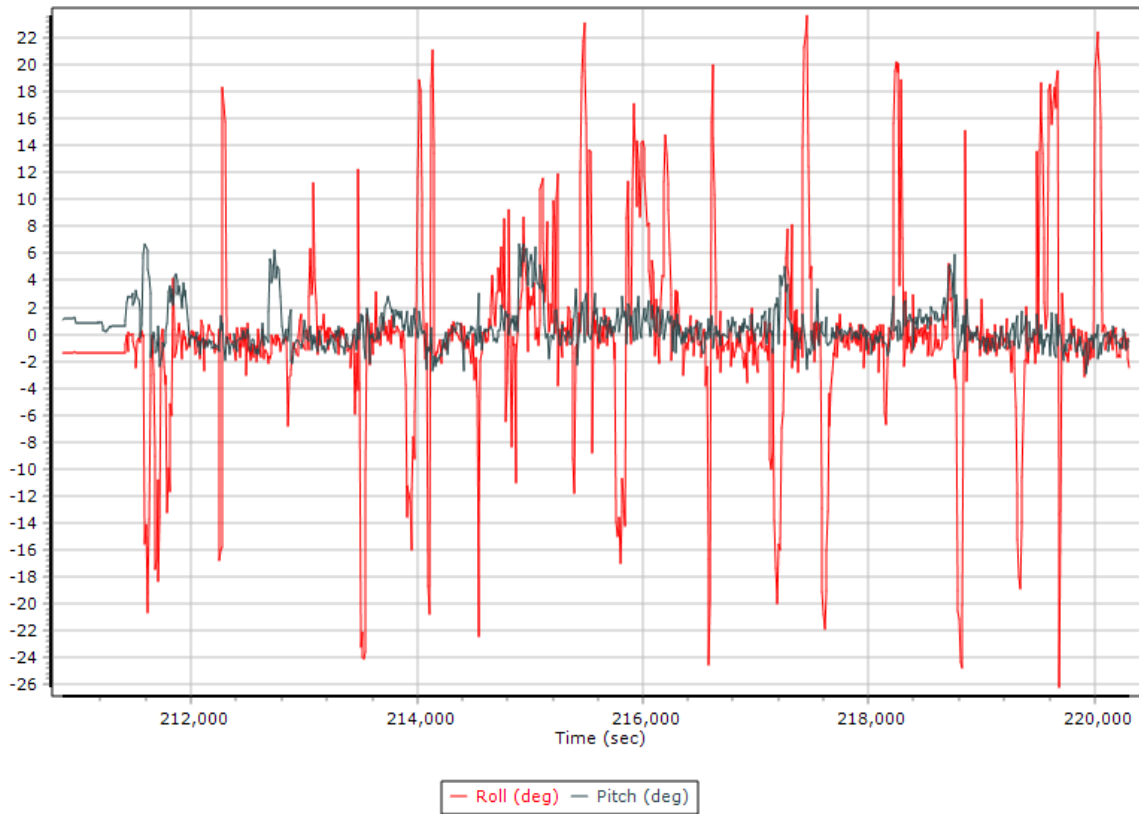
Stabilized Mount to Primary GNSS Lever Arm	Aircraft to Stabilized Mount Mounting Angles
X: -0.049 m	X: 0.000 deg
Y: 0.003 m	Y: 0.000 deg
Z: -1.230 m	Z: 0.000 deg

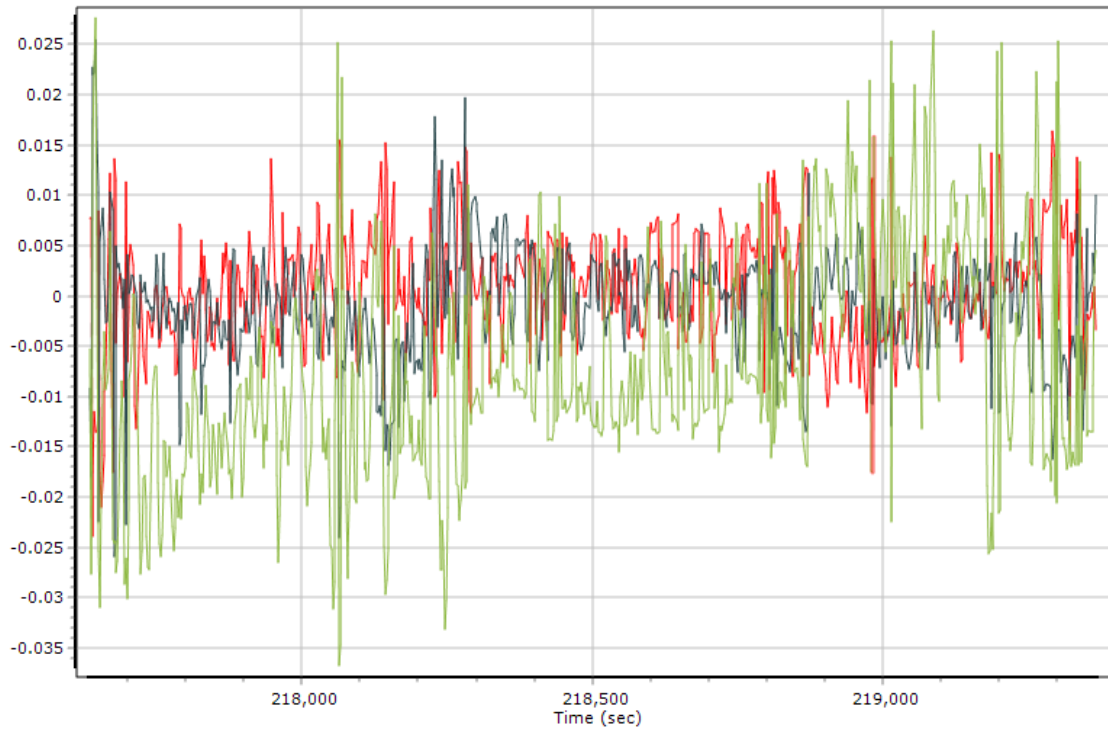
Standard Deviation: <3cm 10cm 50cm 1m 10m

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

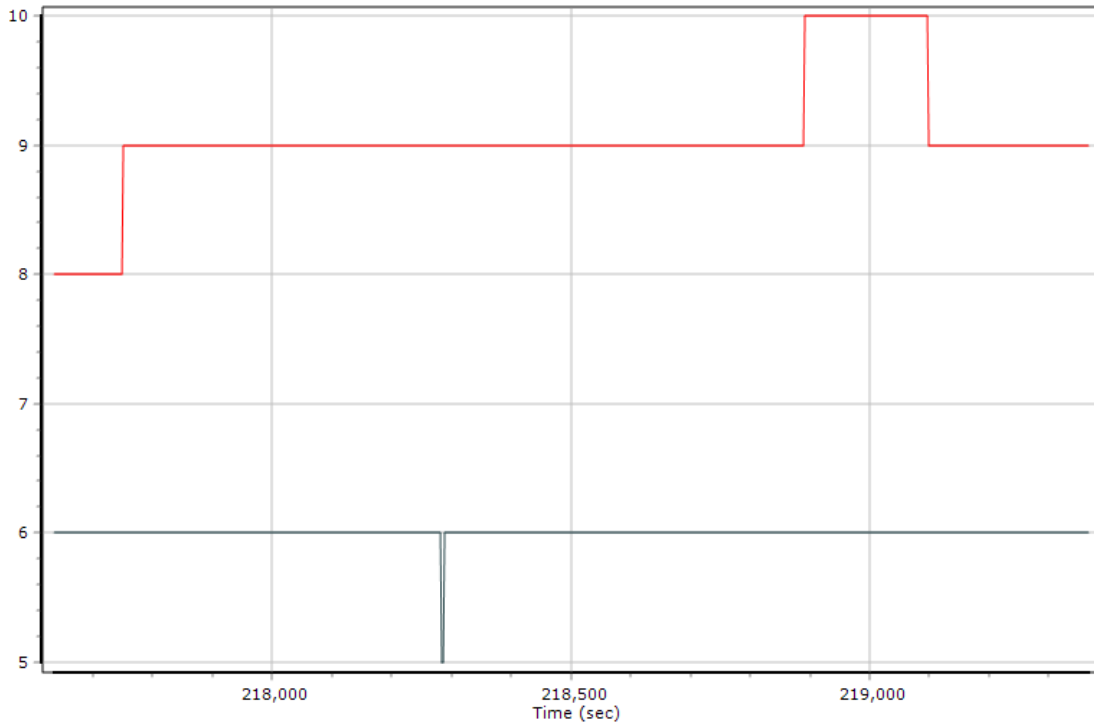
OK Cancel



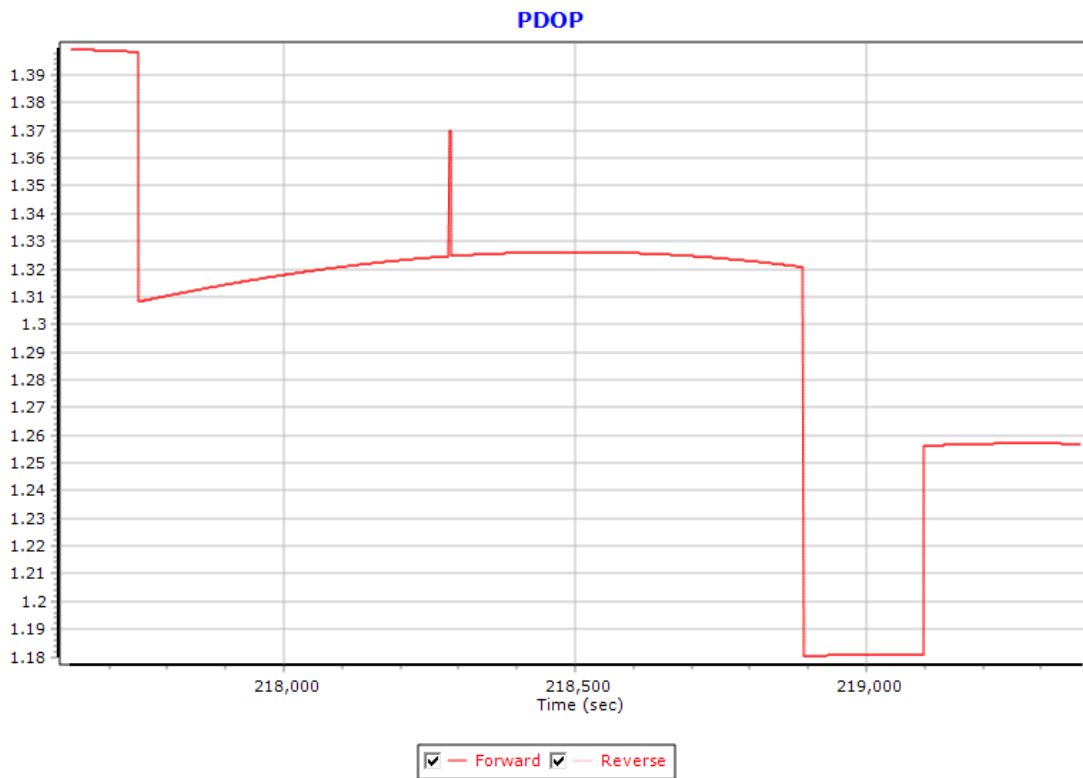
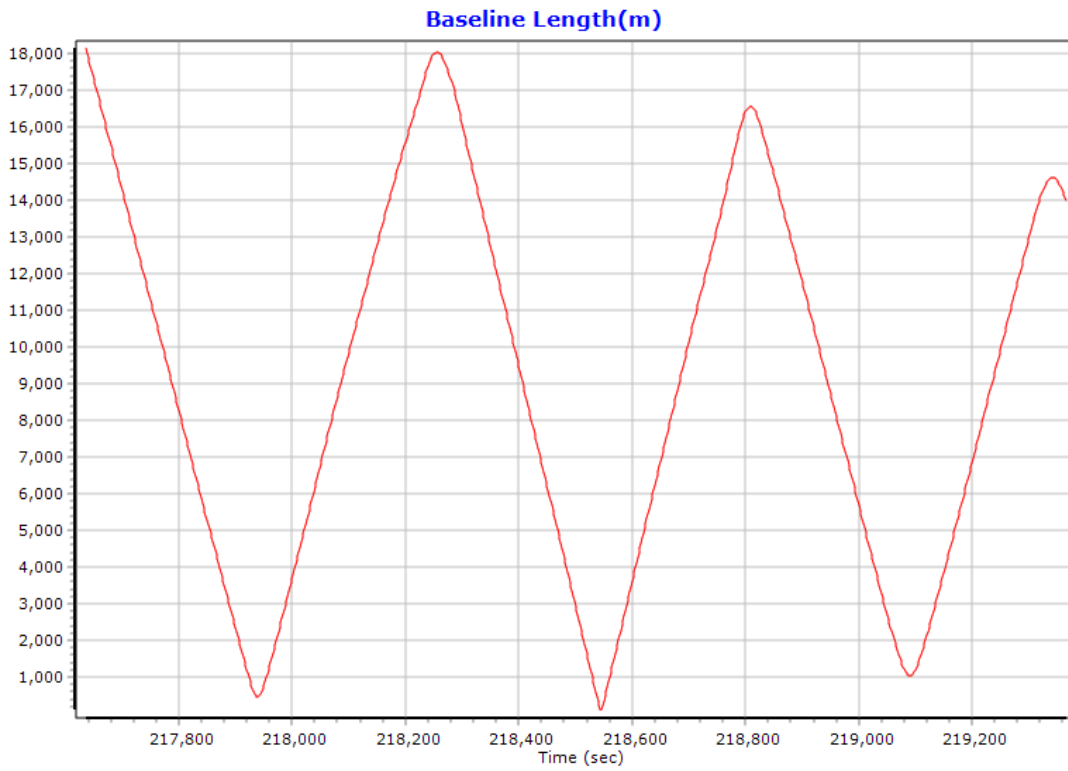




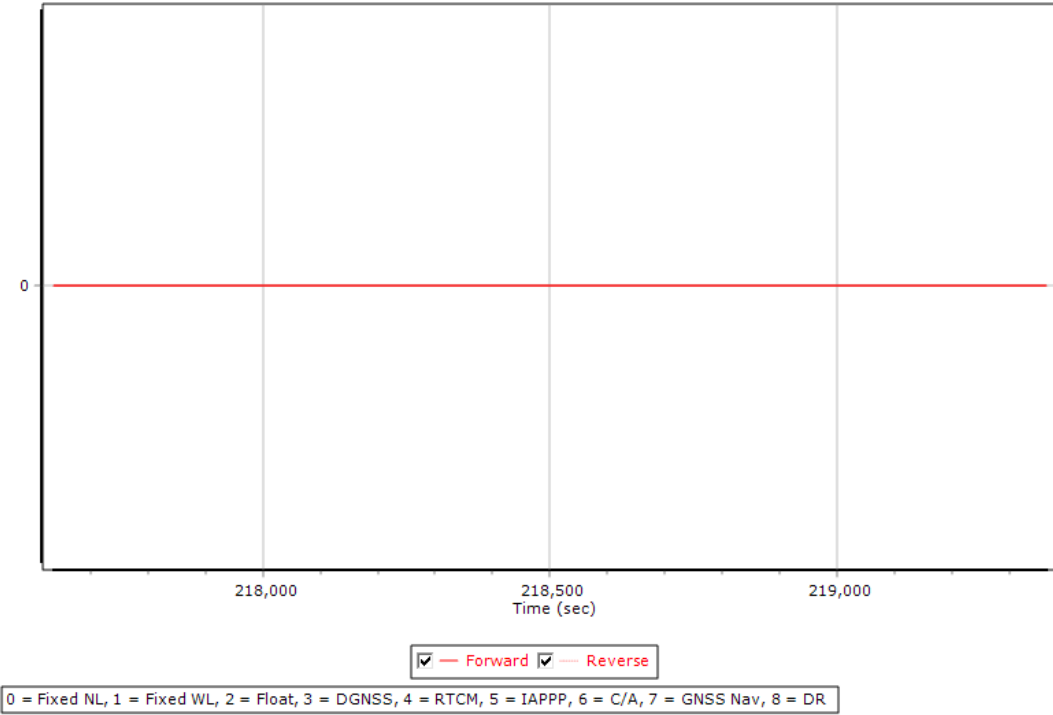
— North (m) — East (m) — Down (m) — DR mode



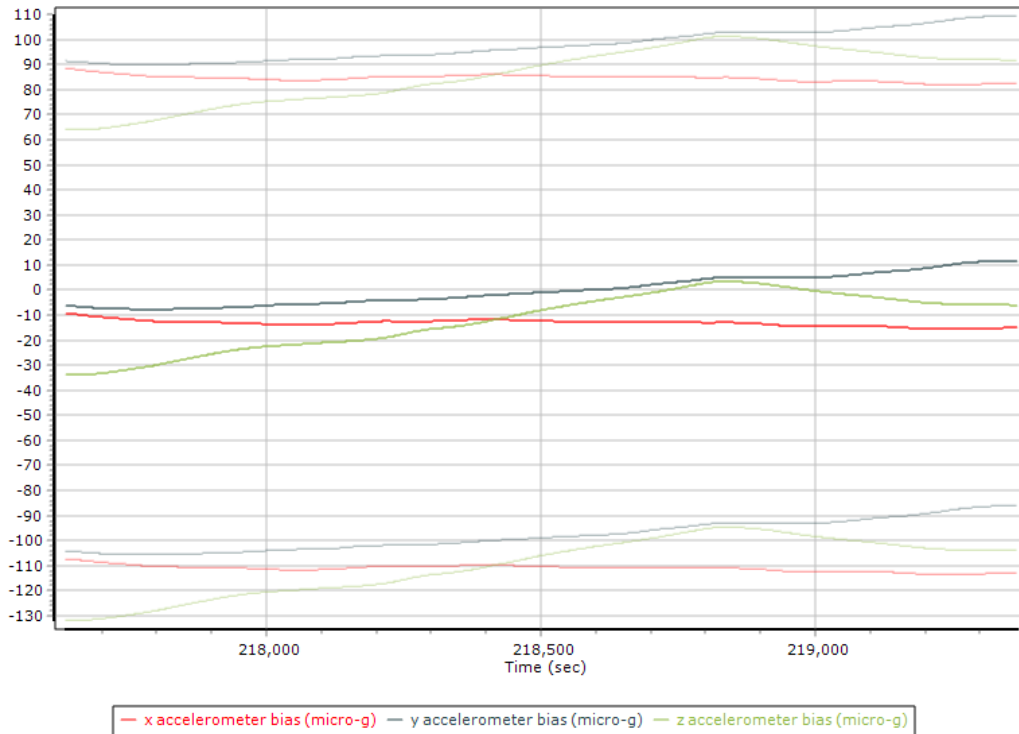
— Number of GPS Satellites — Number of GLONASS Satellites

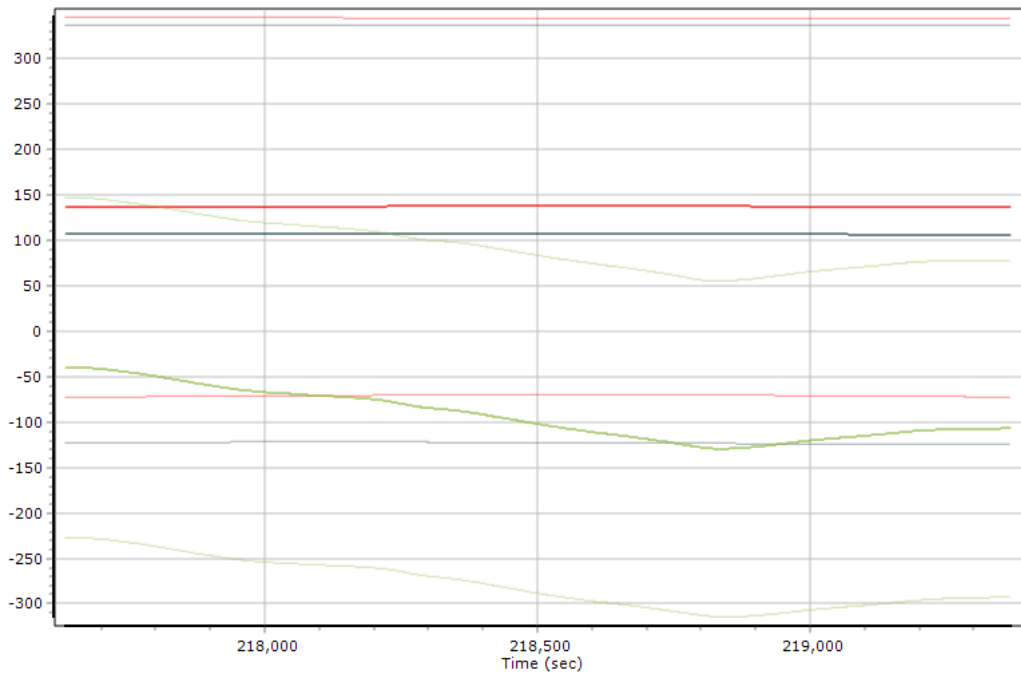


Processing Mode

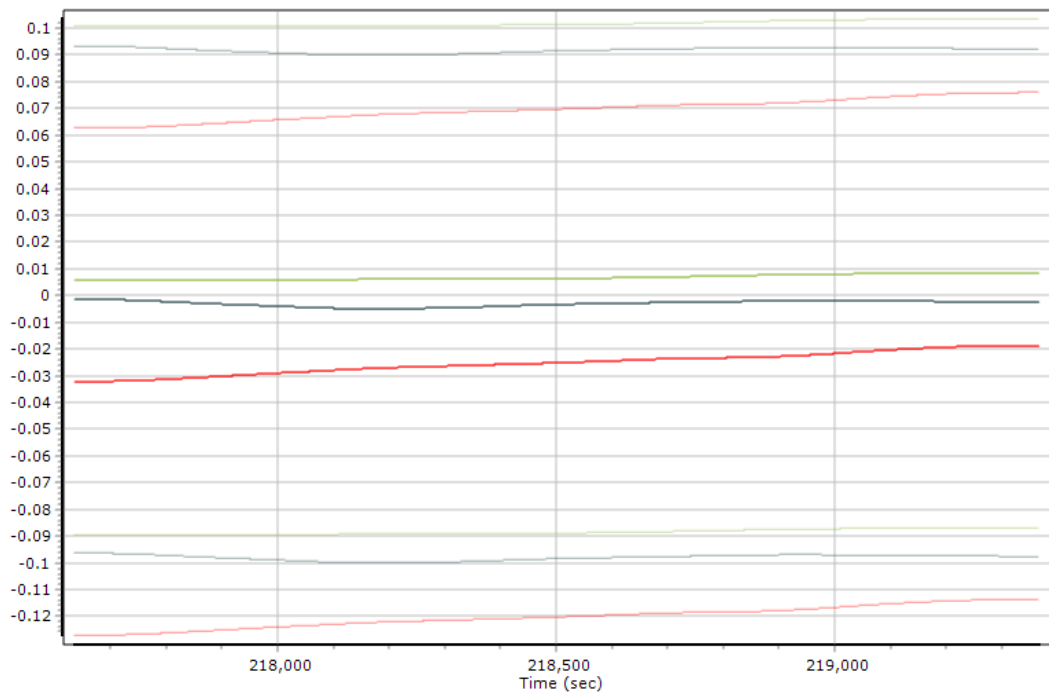


Sensor Errors

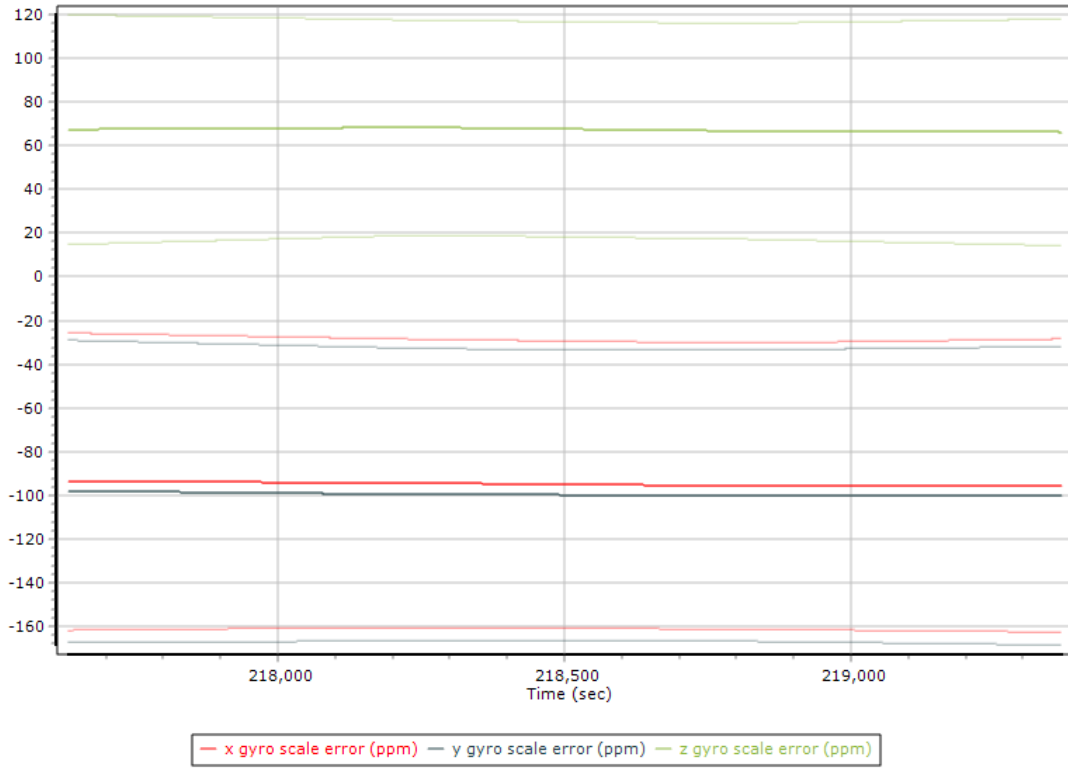




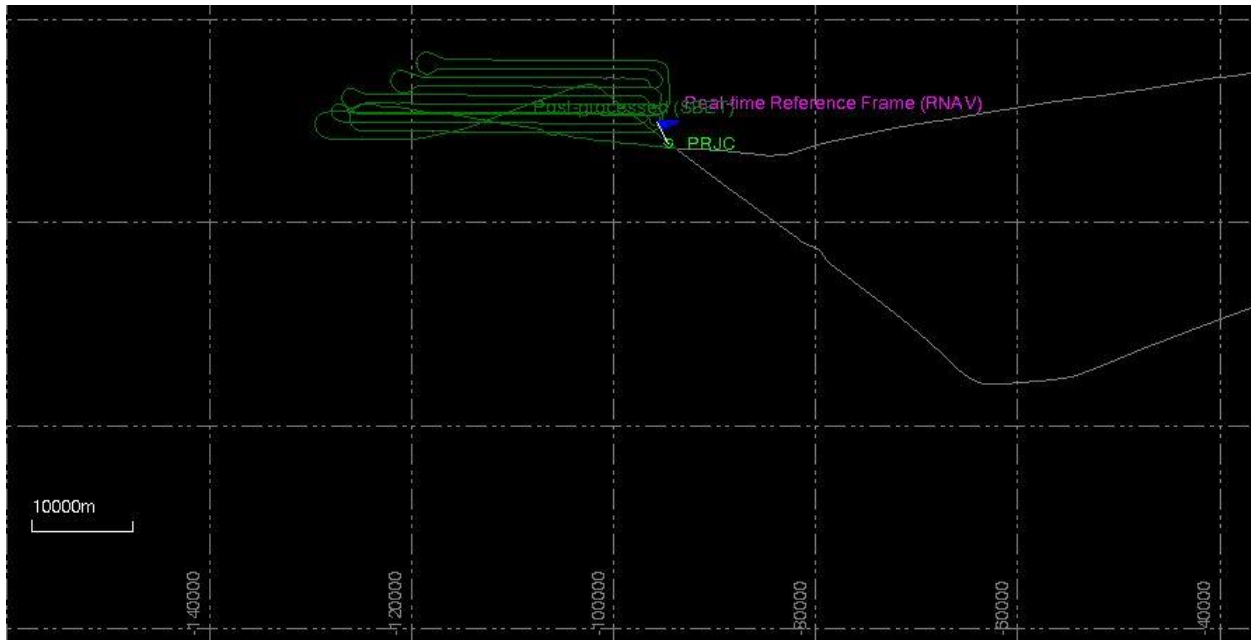
x accelerometer scale error (ppm) y accelerometer scale error (ppm) z accelerometer scale error (ppm)

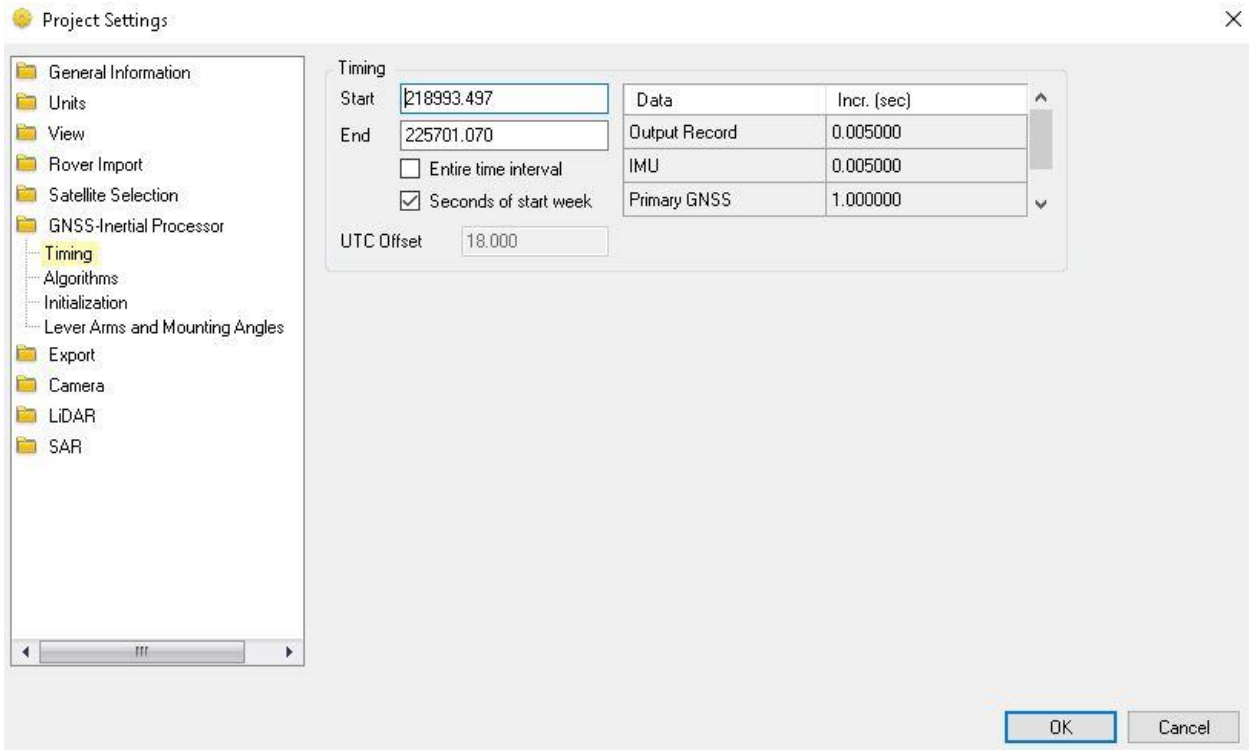
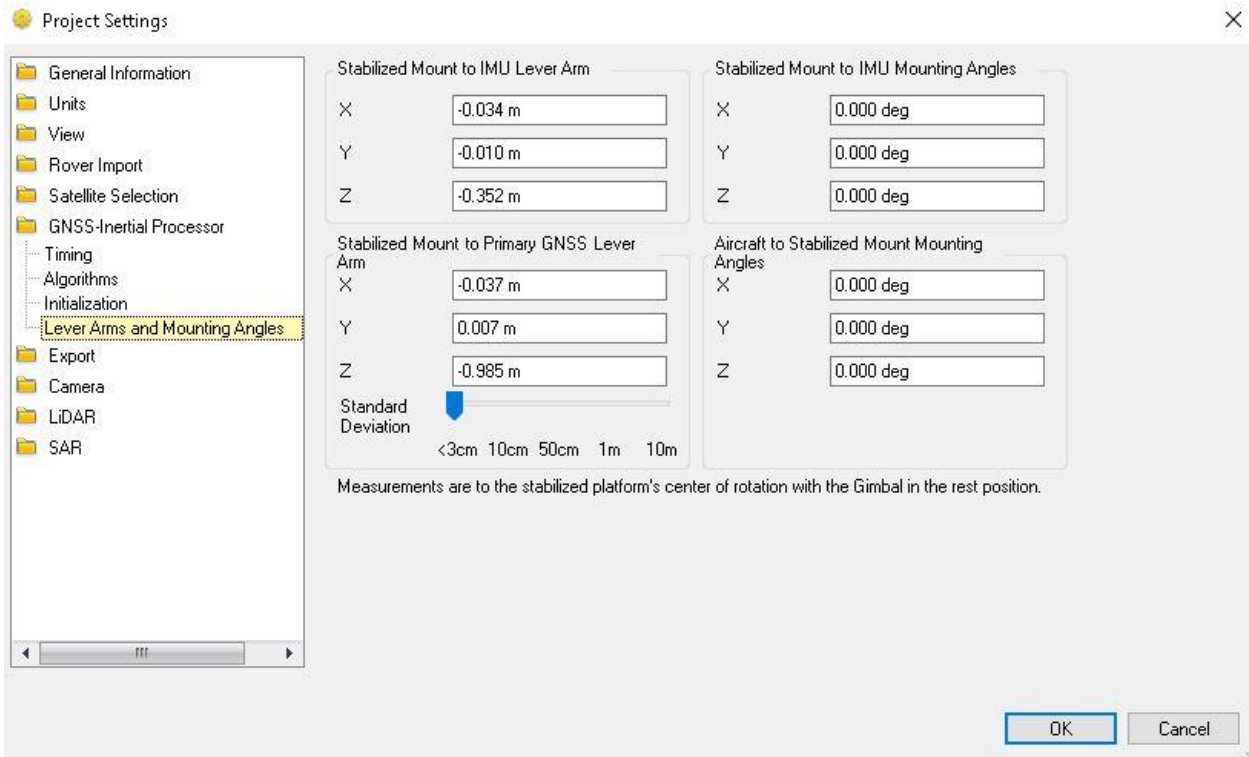


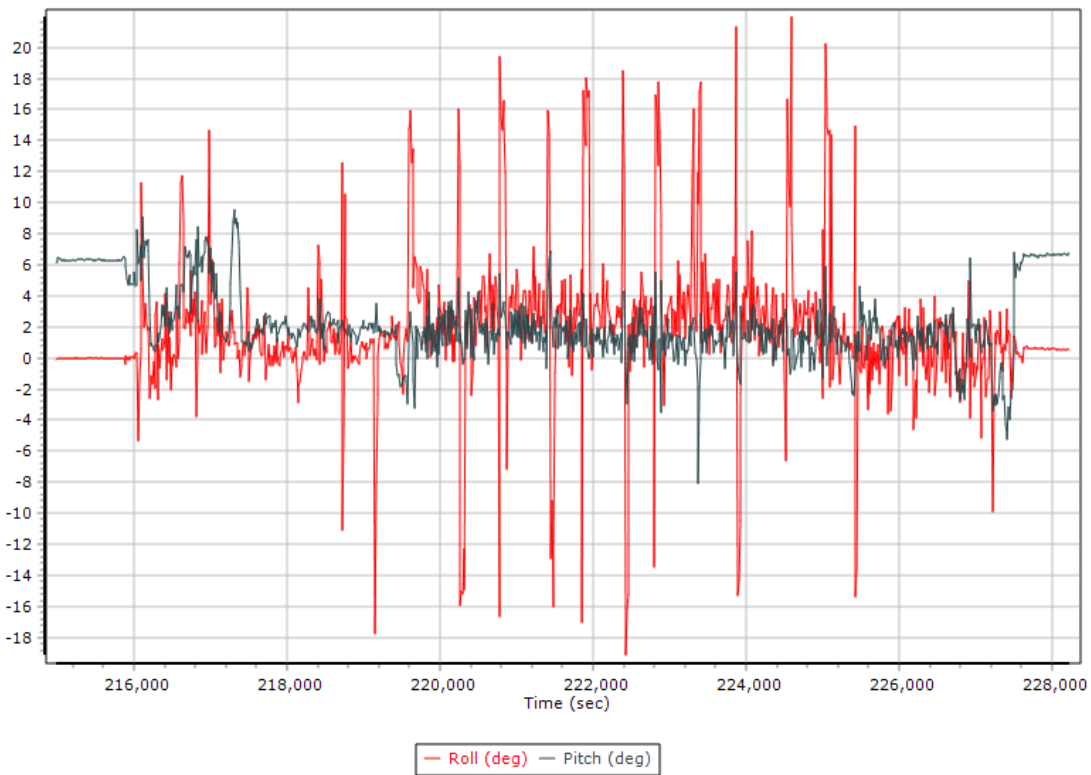
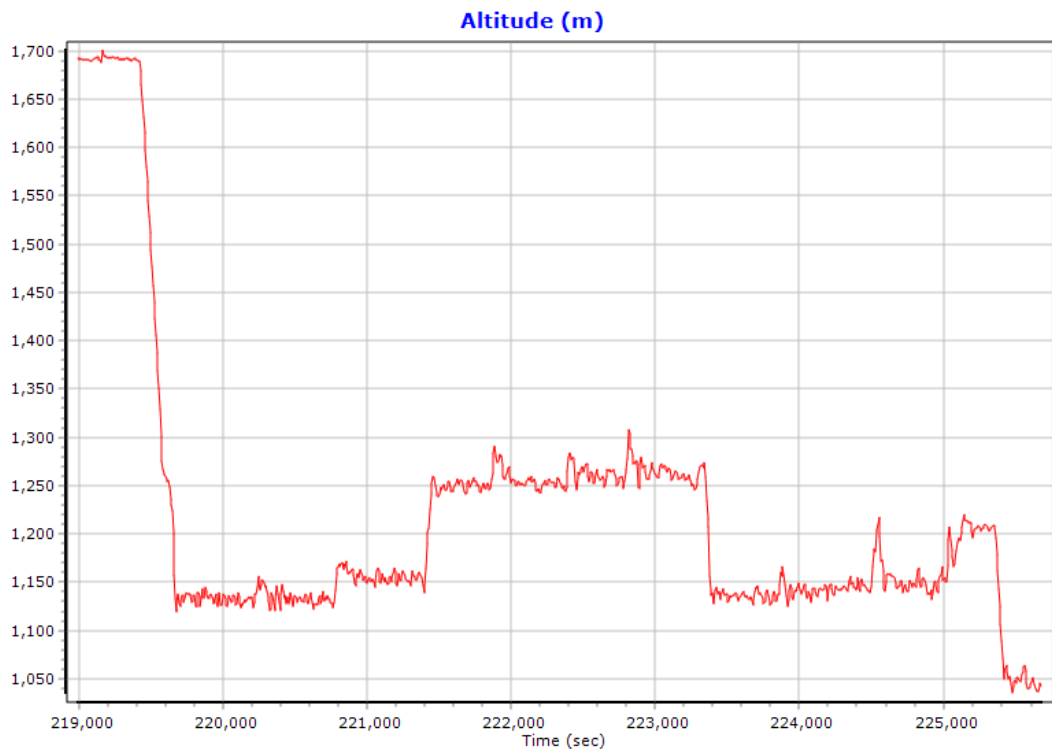
x gyro bias (deg/hr) y gyro bias (deg/hr) z gyro bias (deg/hr)

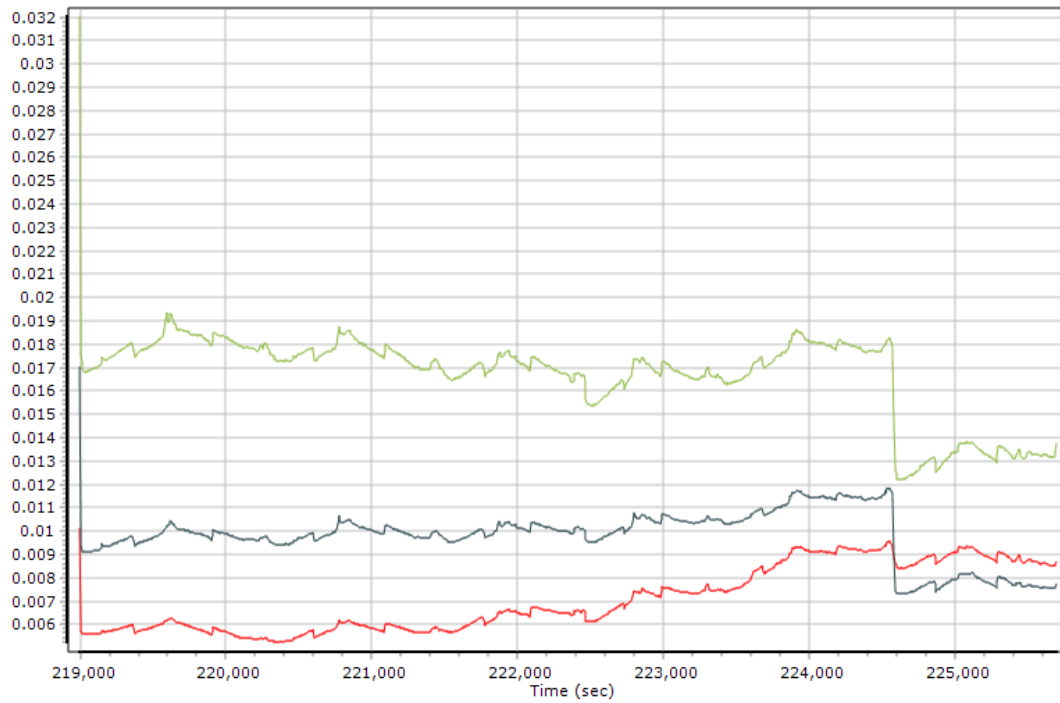


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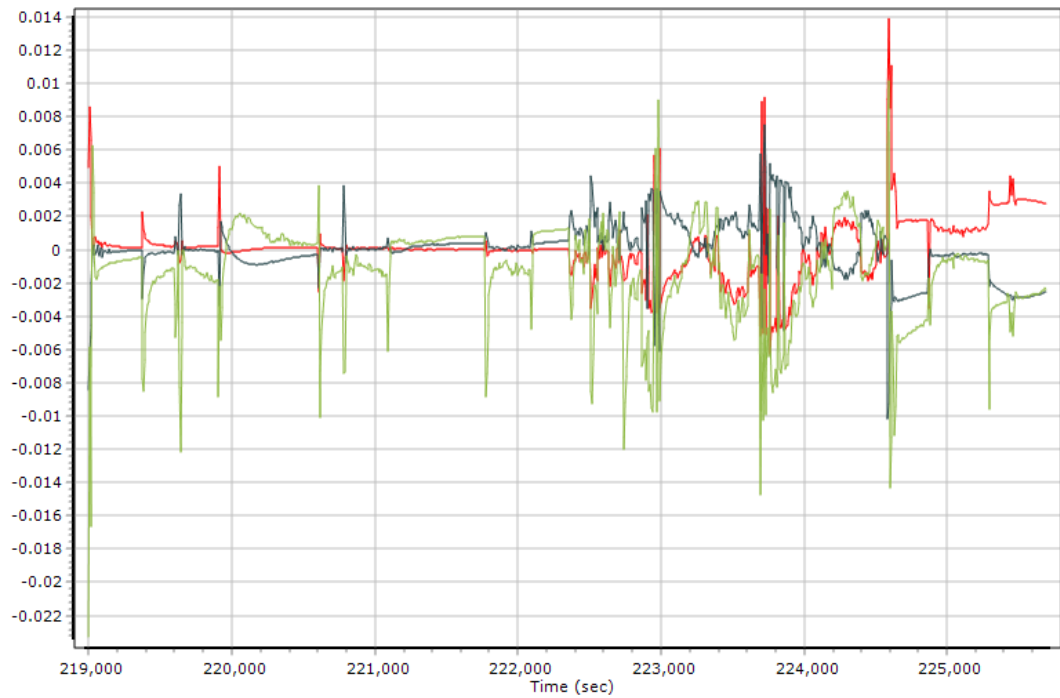




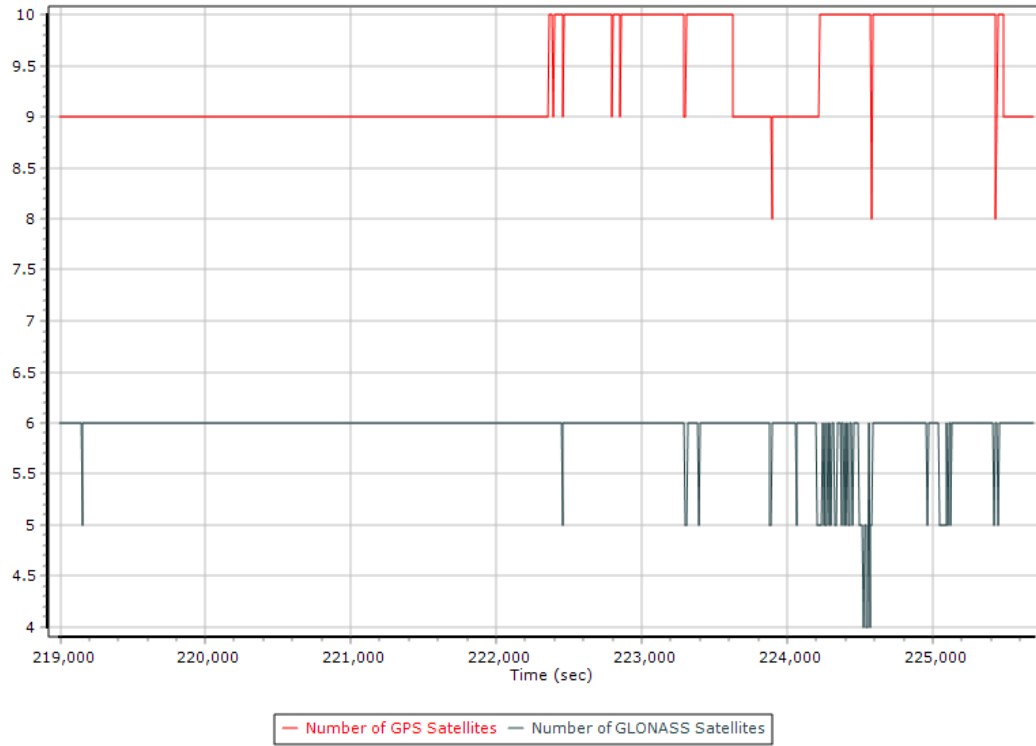




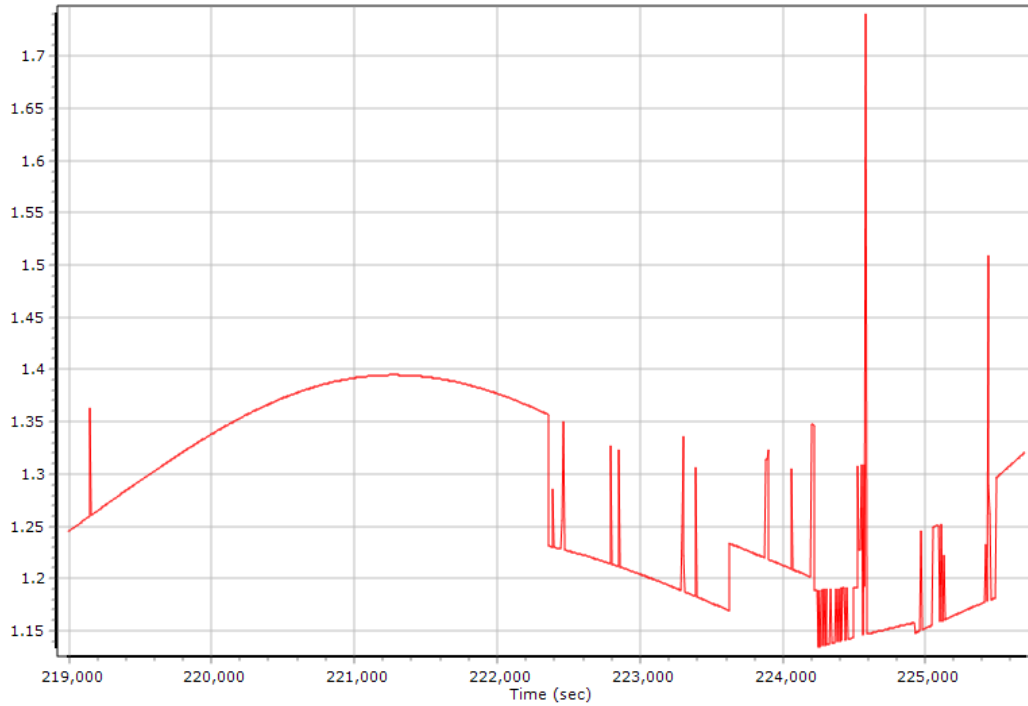
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



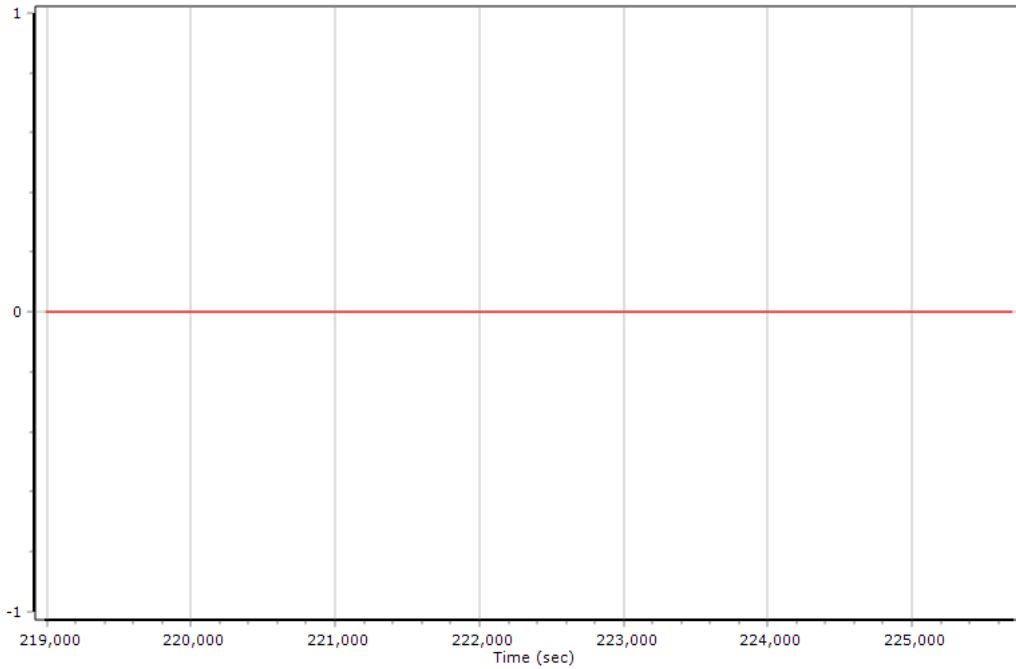
— North (m) — East (m) — Down (m) — DR mode



PDOP

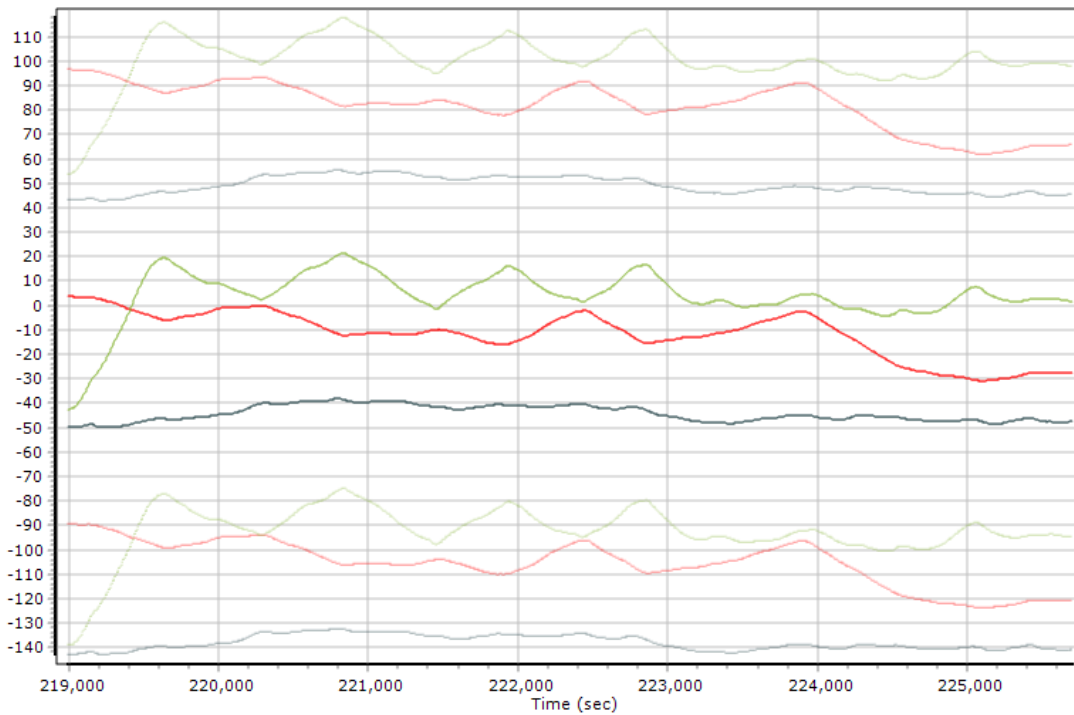


Processing mode

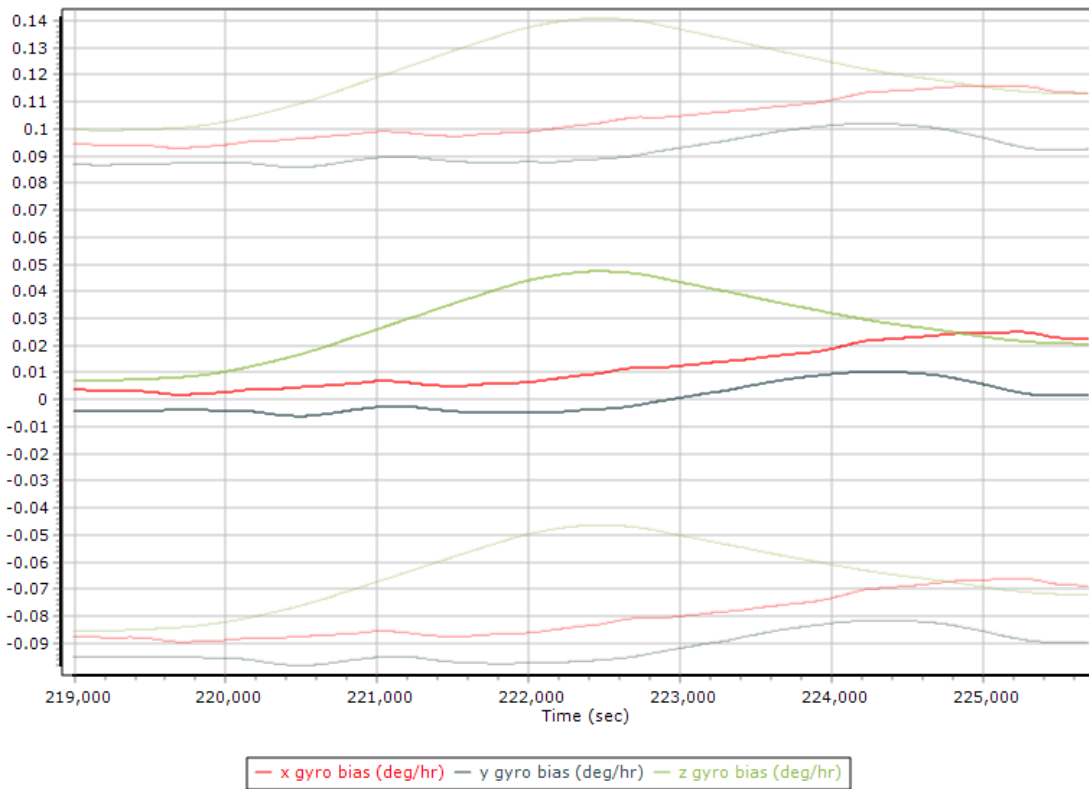
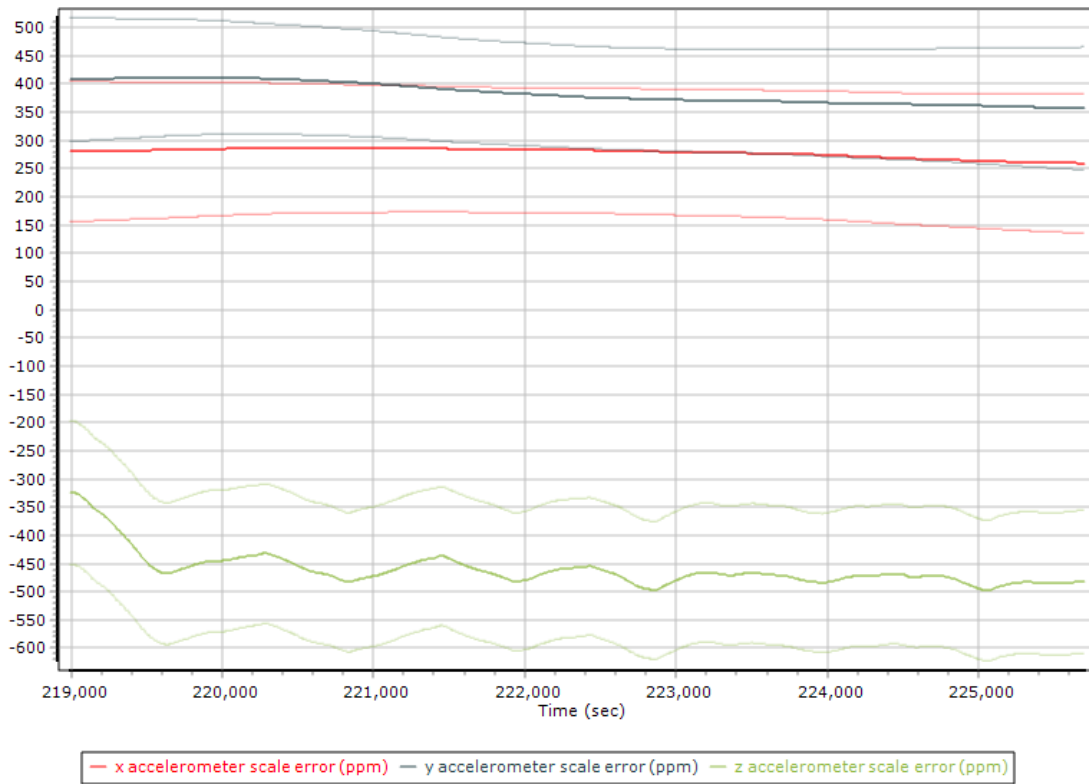


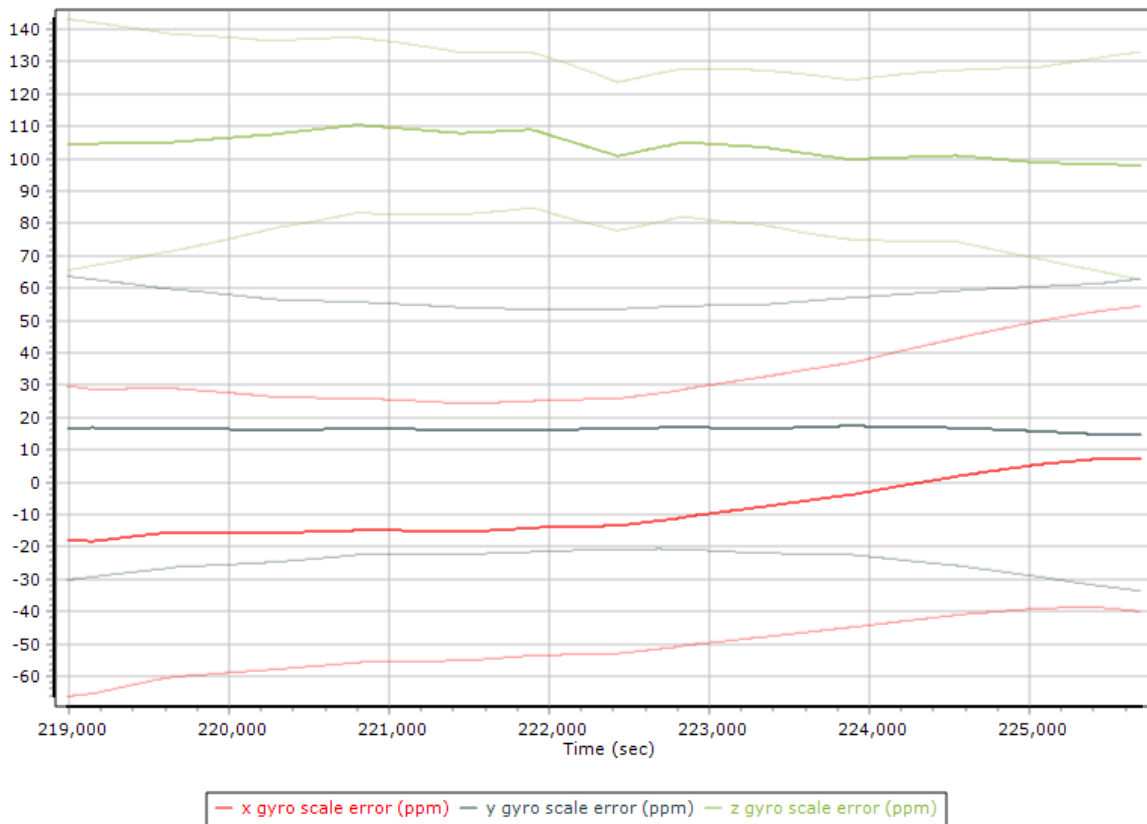
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

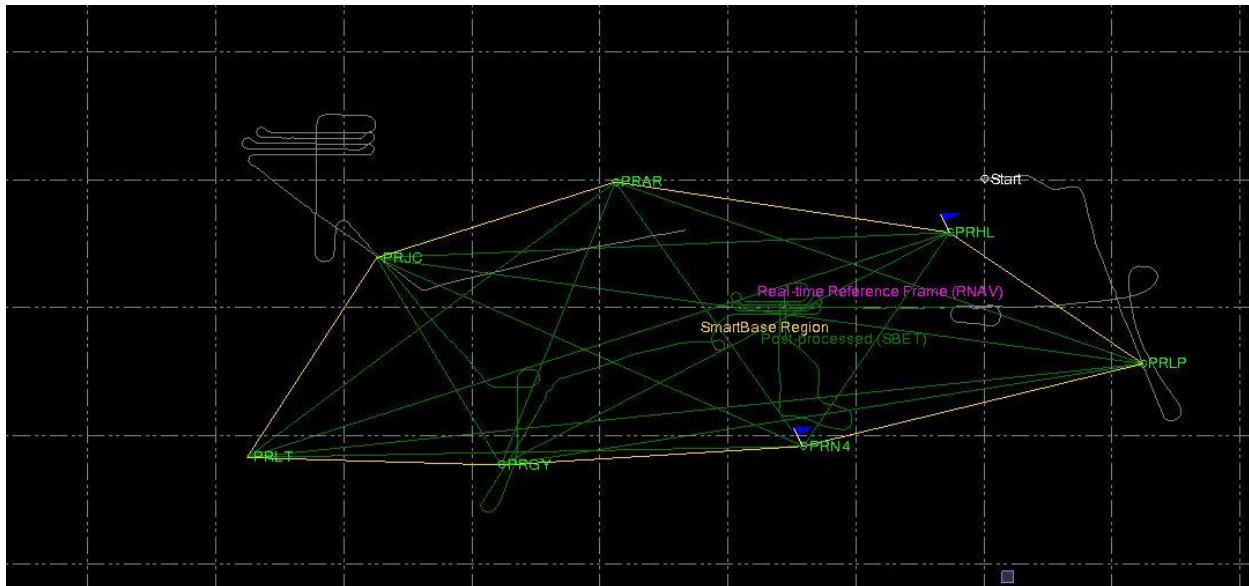


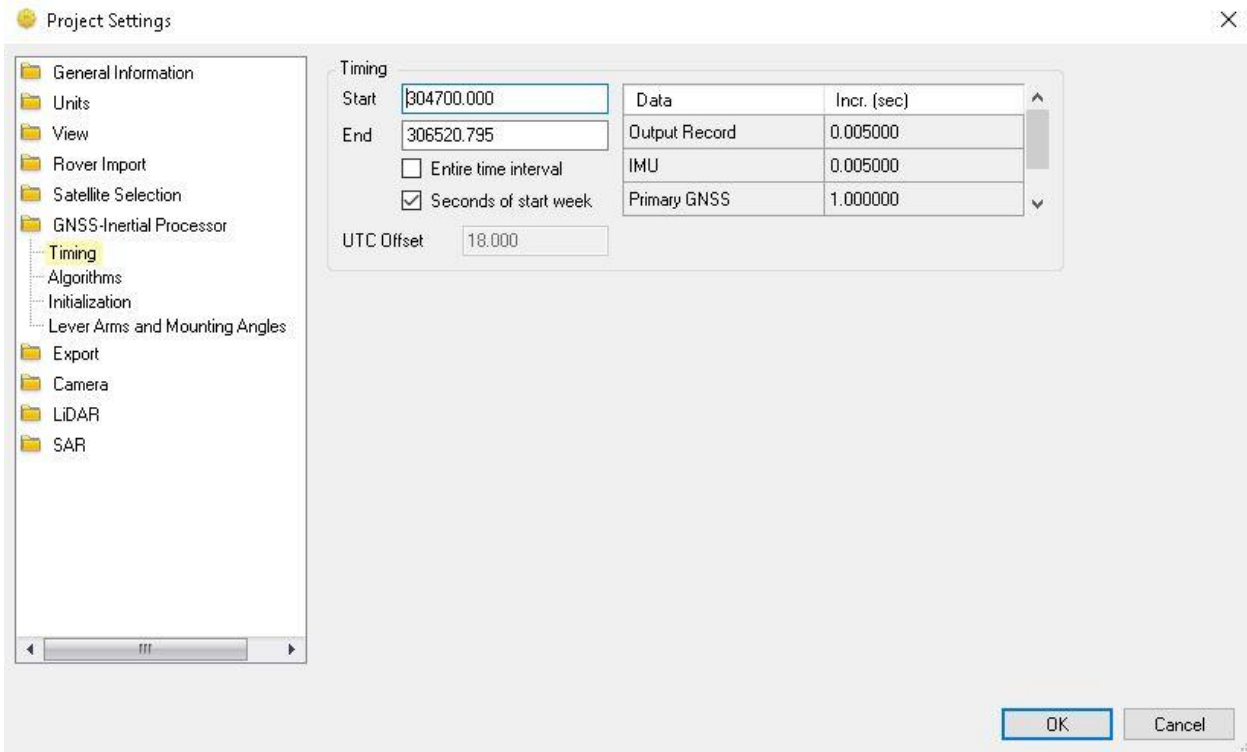
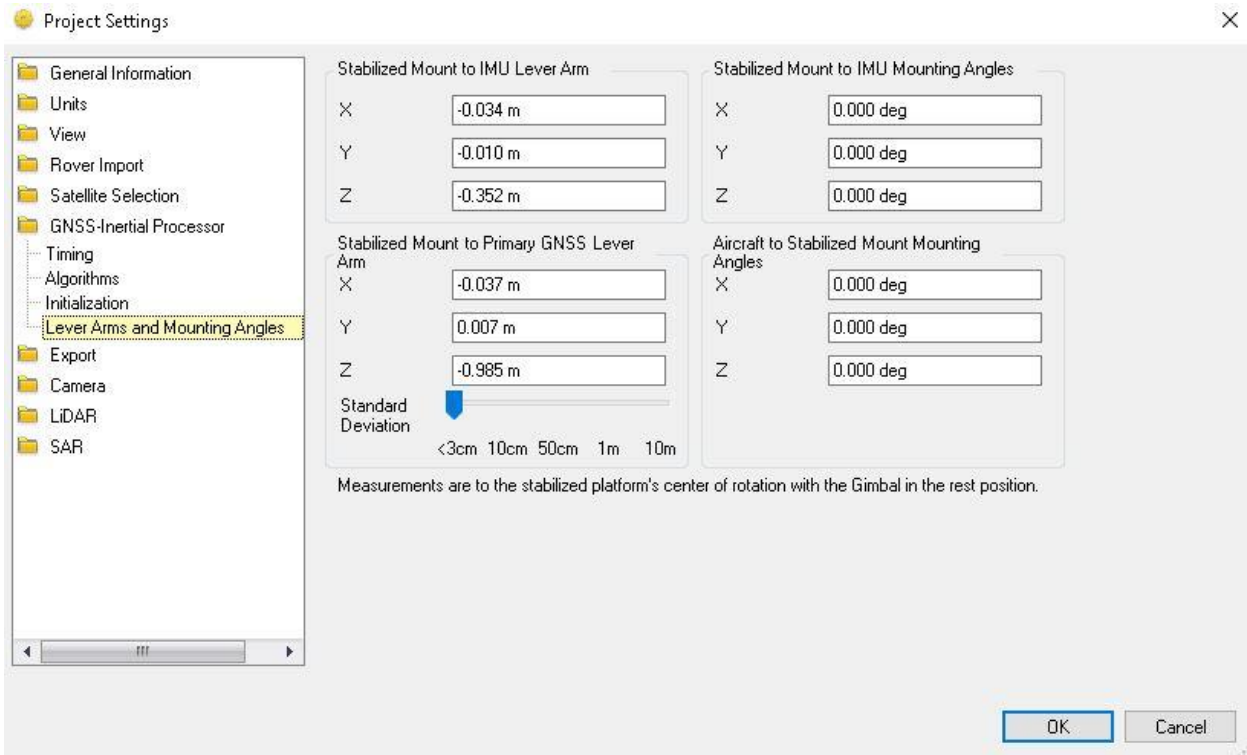
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)

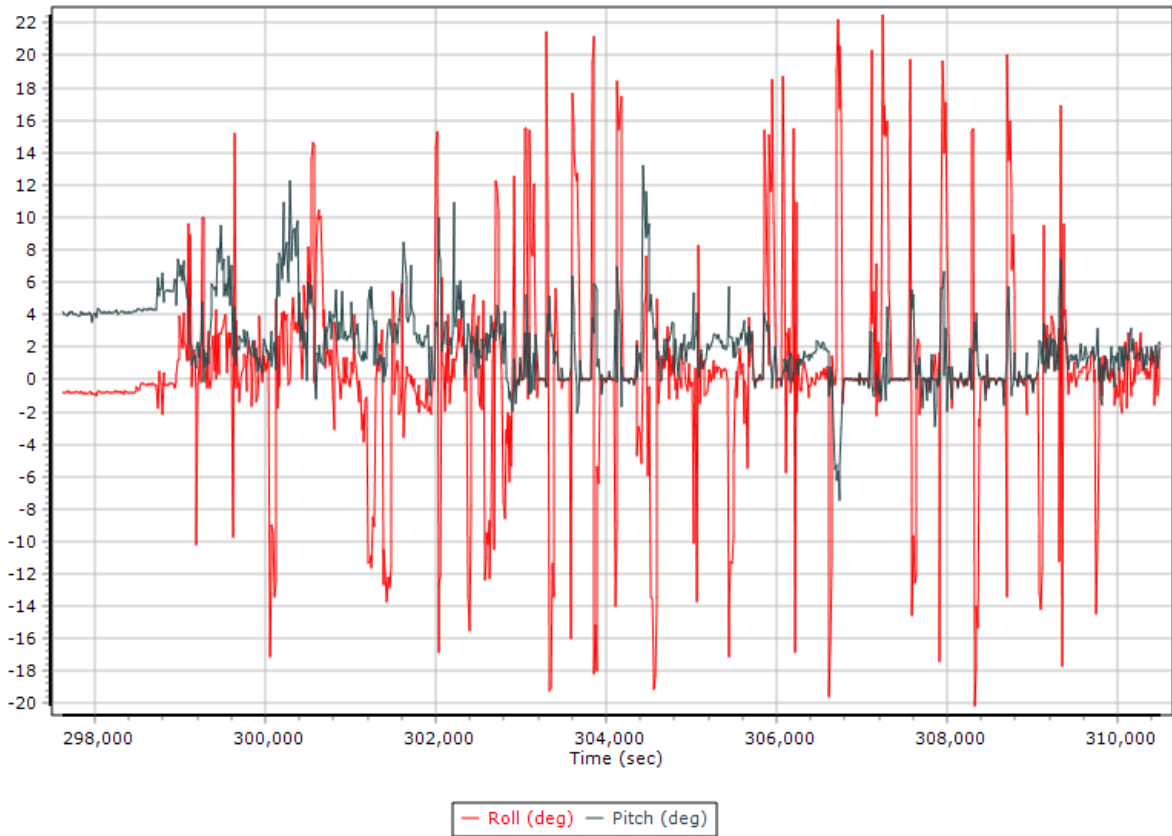
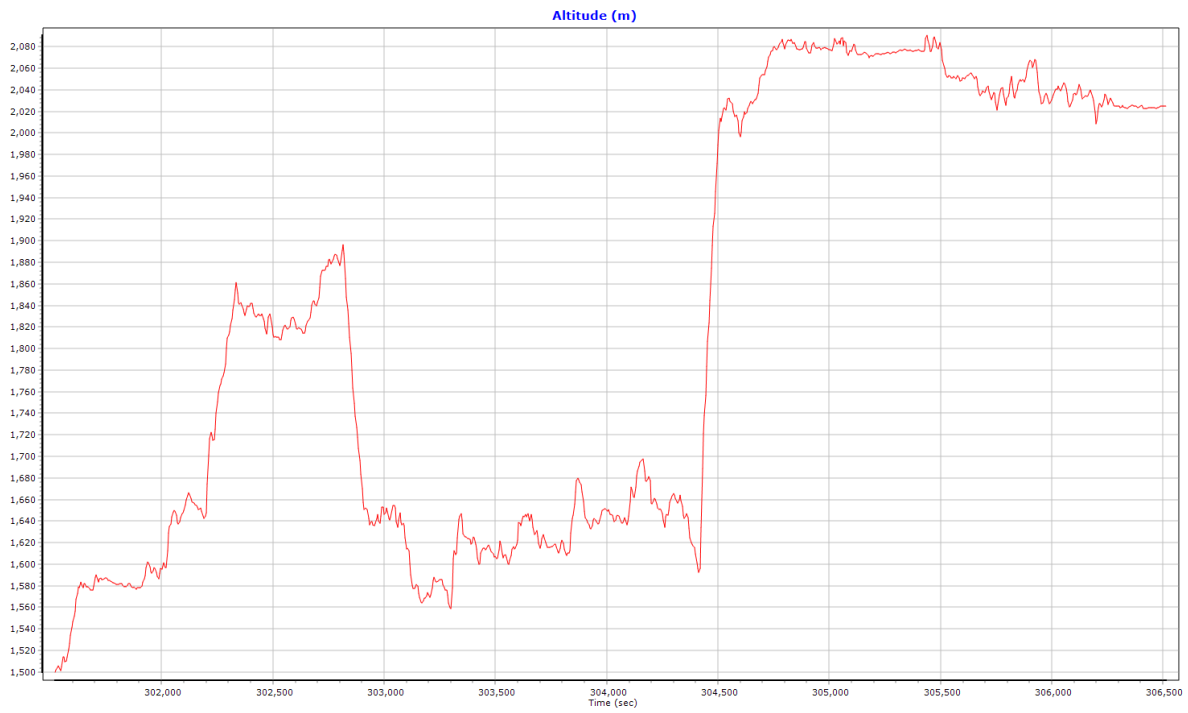


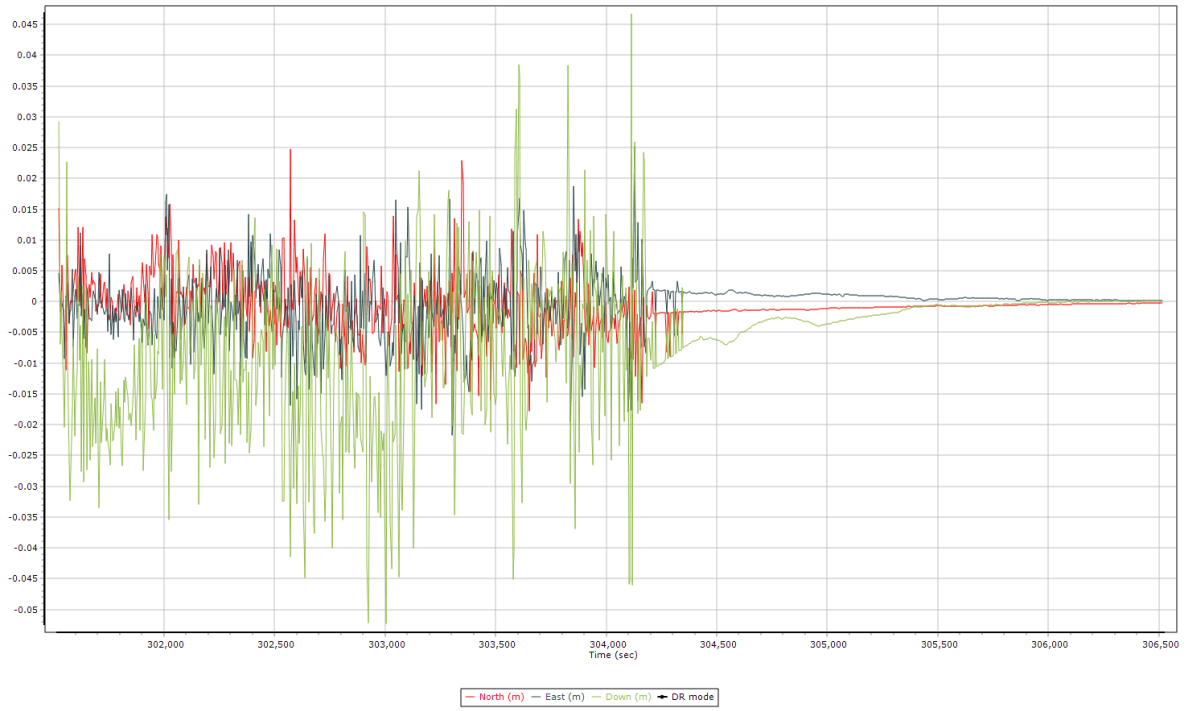
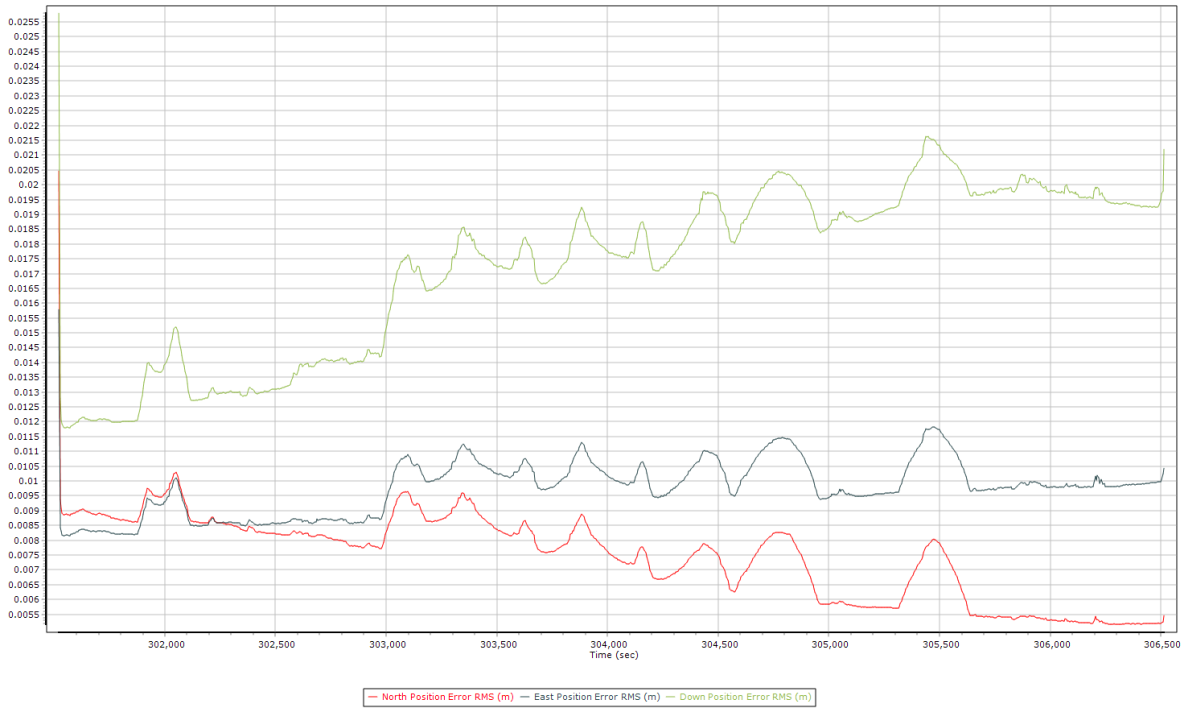


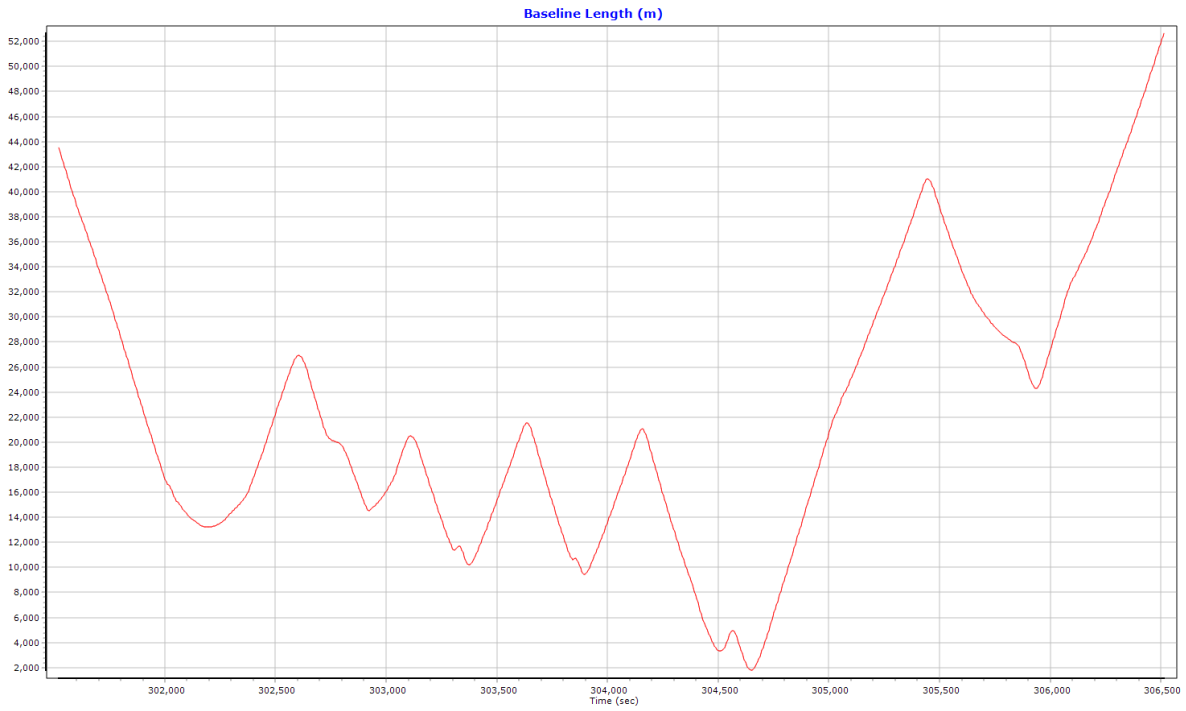
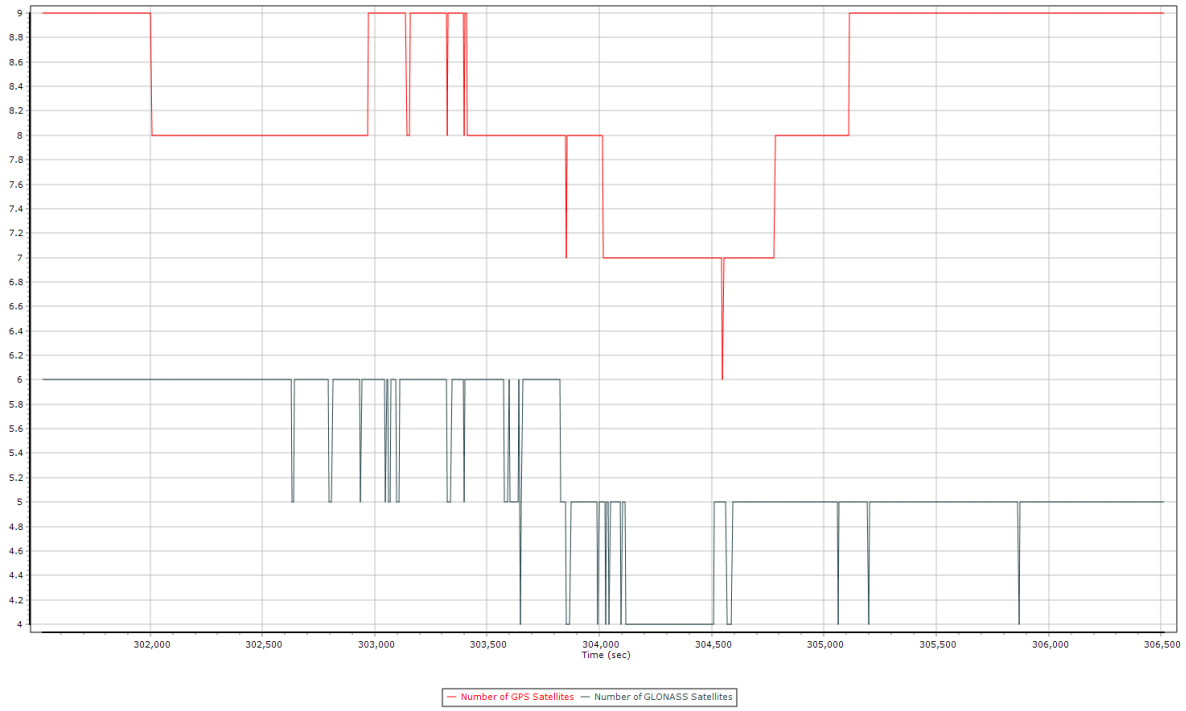
RBV18108A1

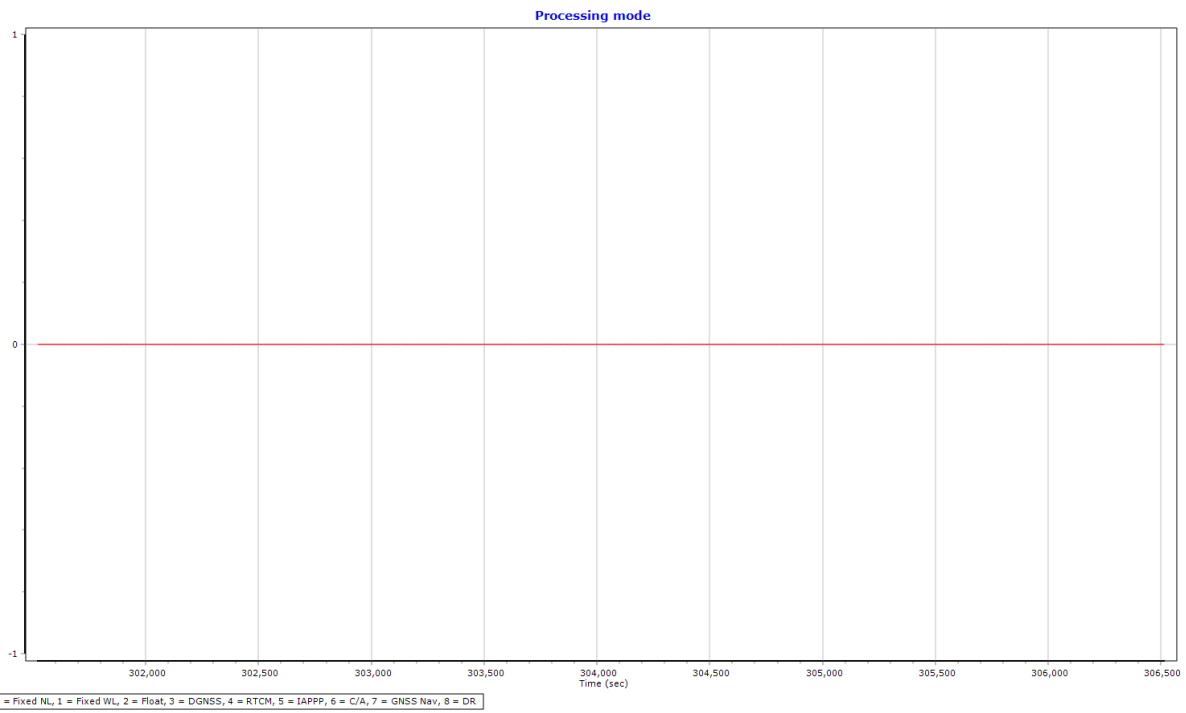
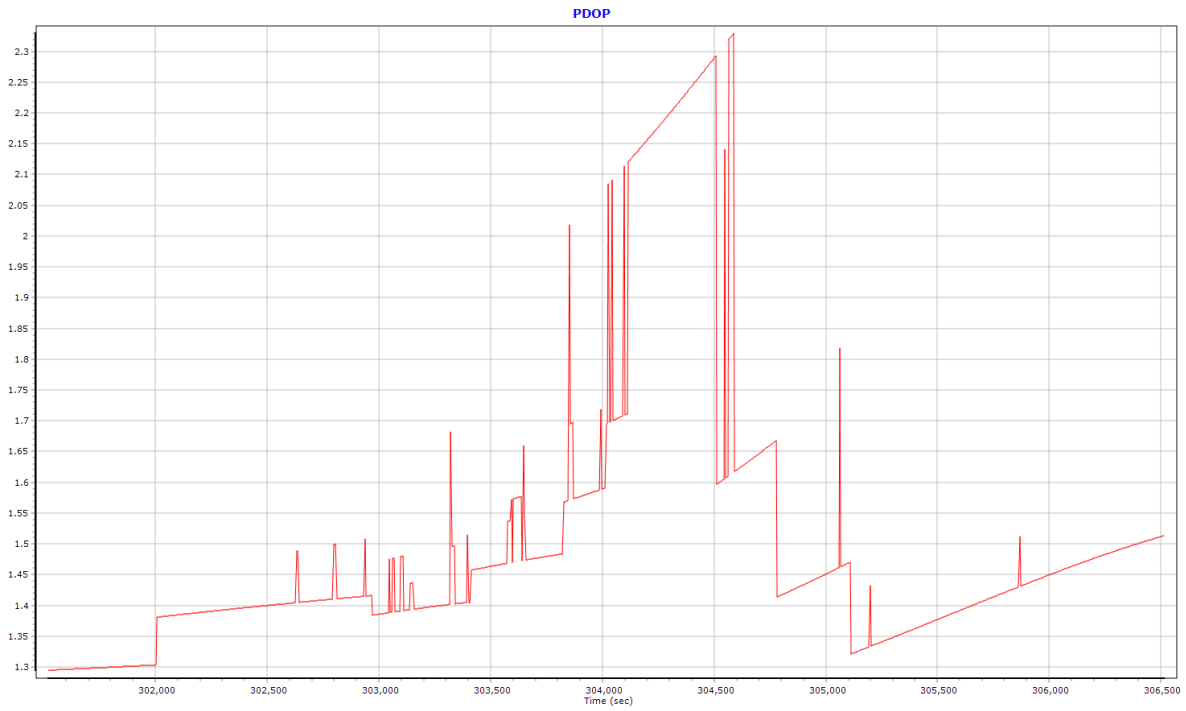




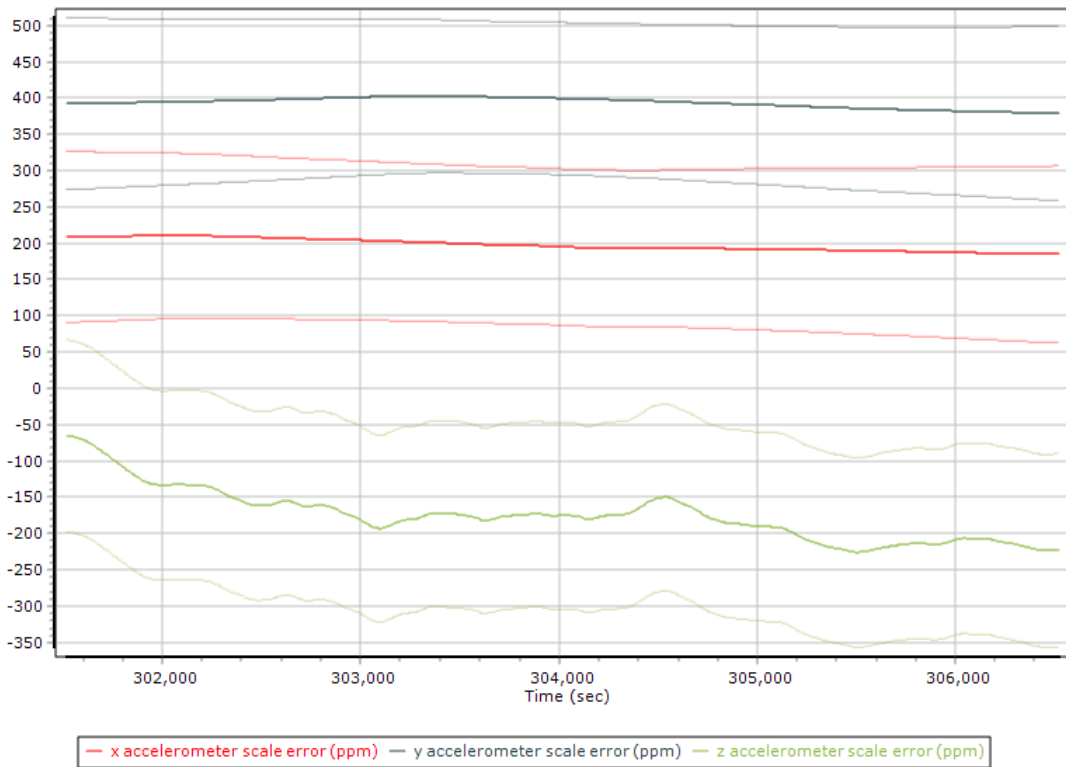
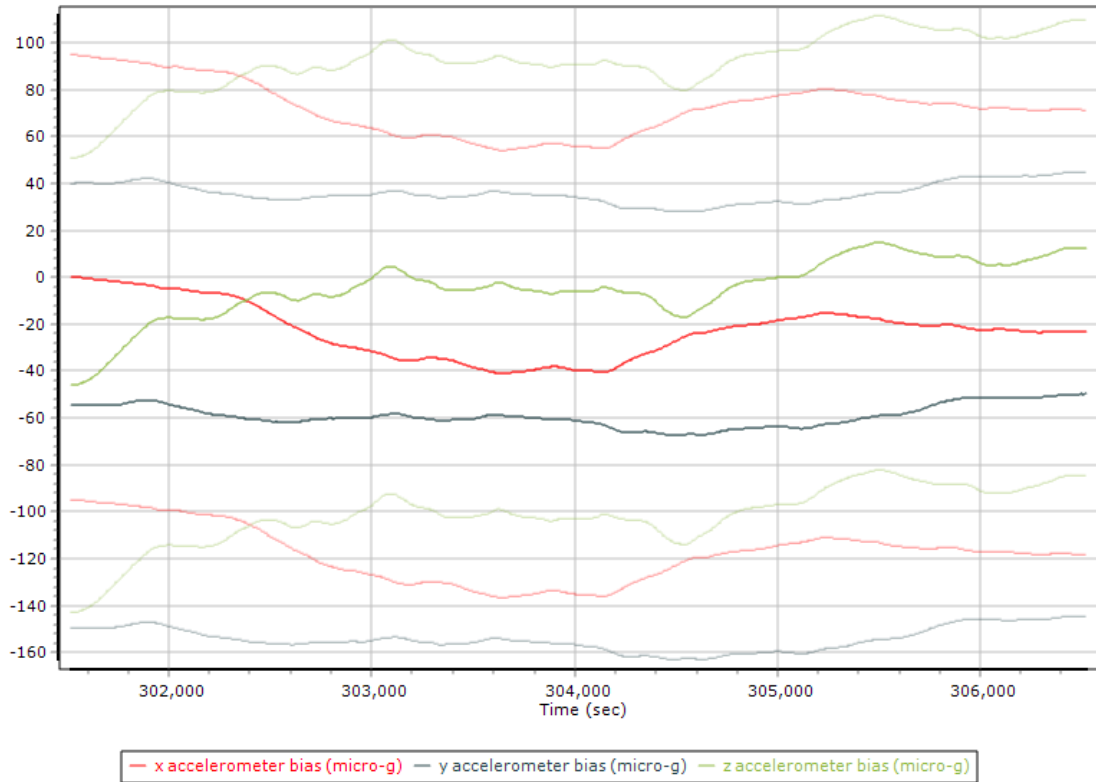


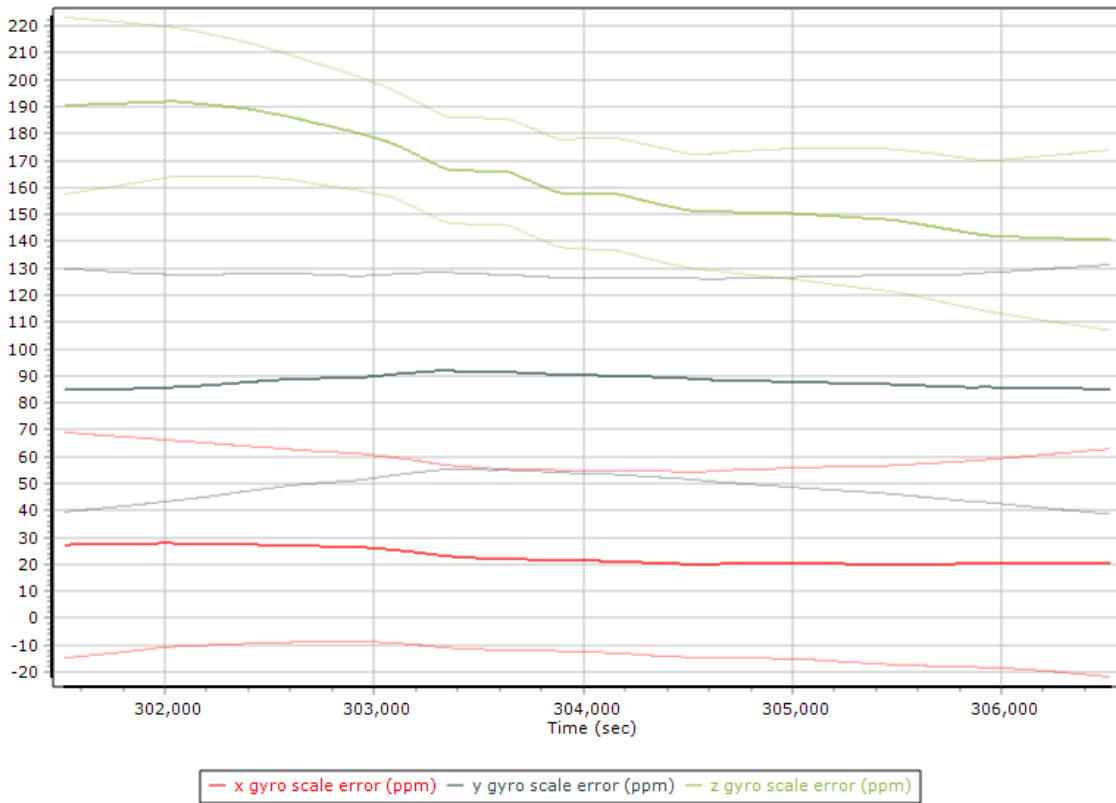
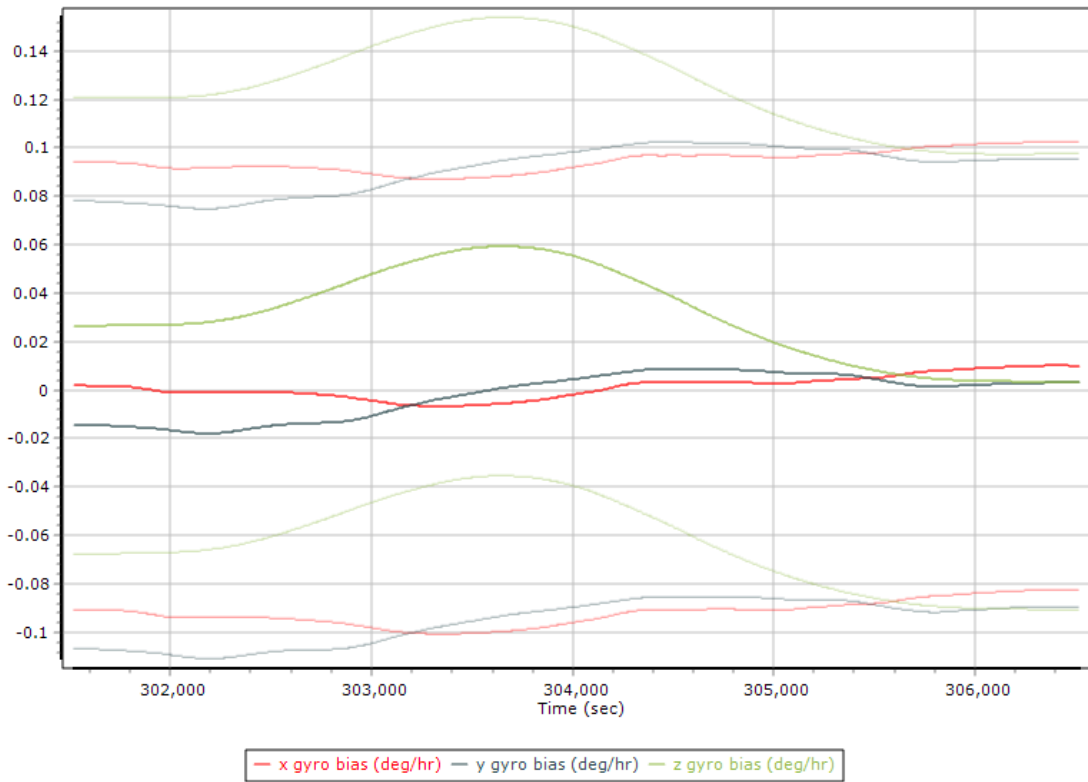




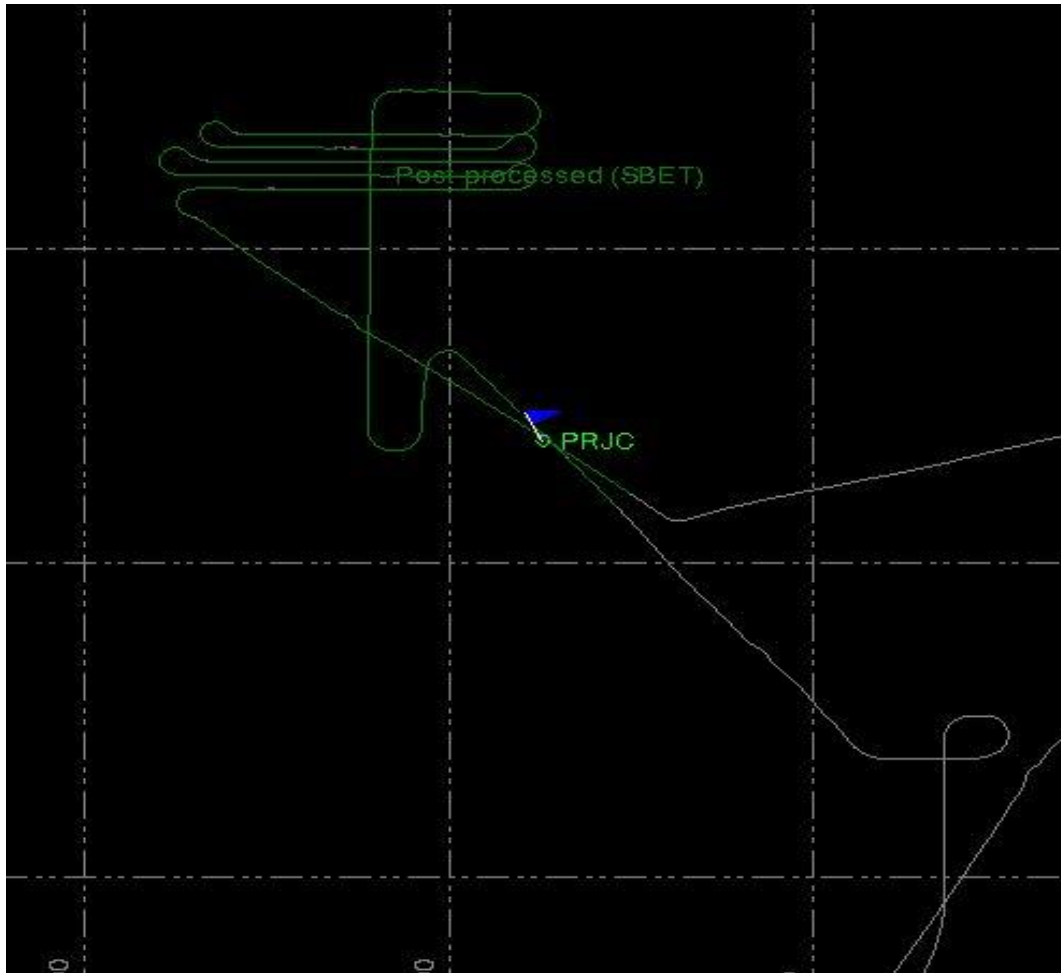


Sensor Errors





RBV18108A2



Project Settings

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	-0.037 m	X	0.000 deg
Y	0.007 m	Y	0.000 deg
Z	-0.985 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
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR

Timing

Start: 306401.767

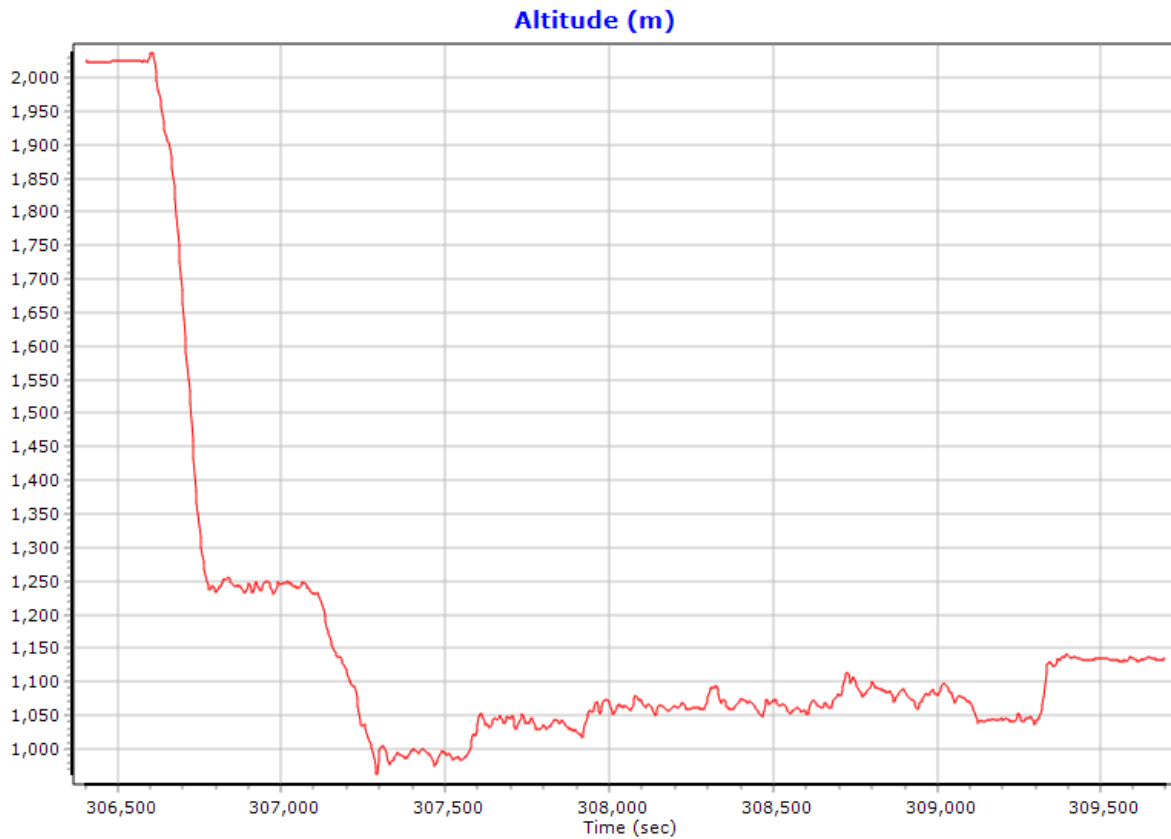
End: 309700.543

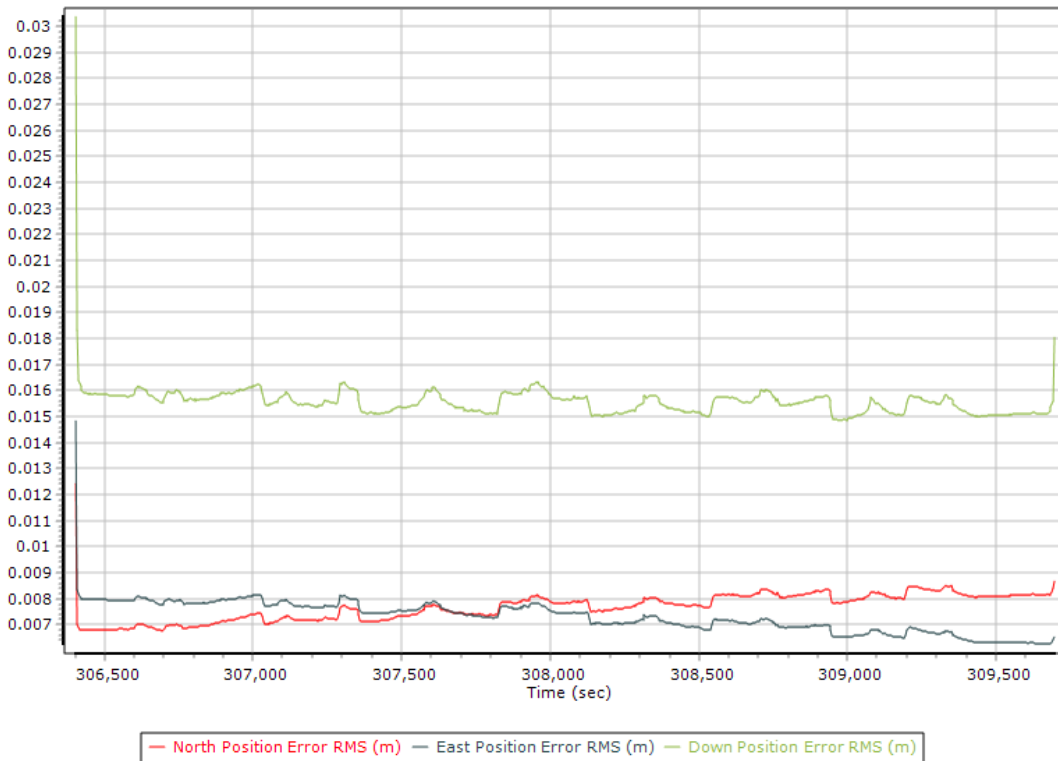
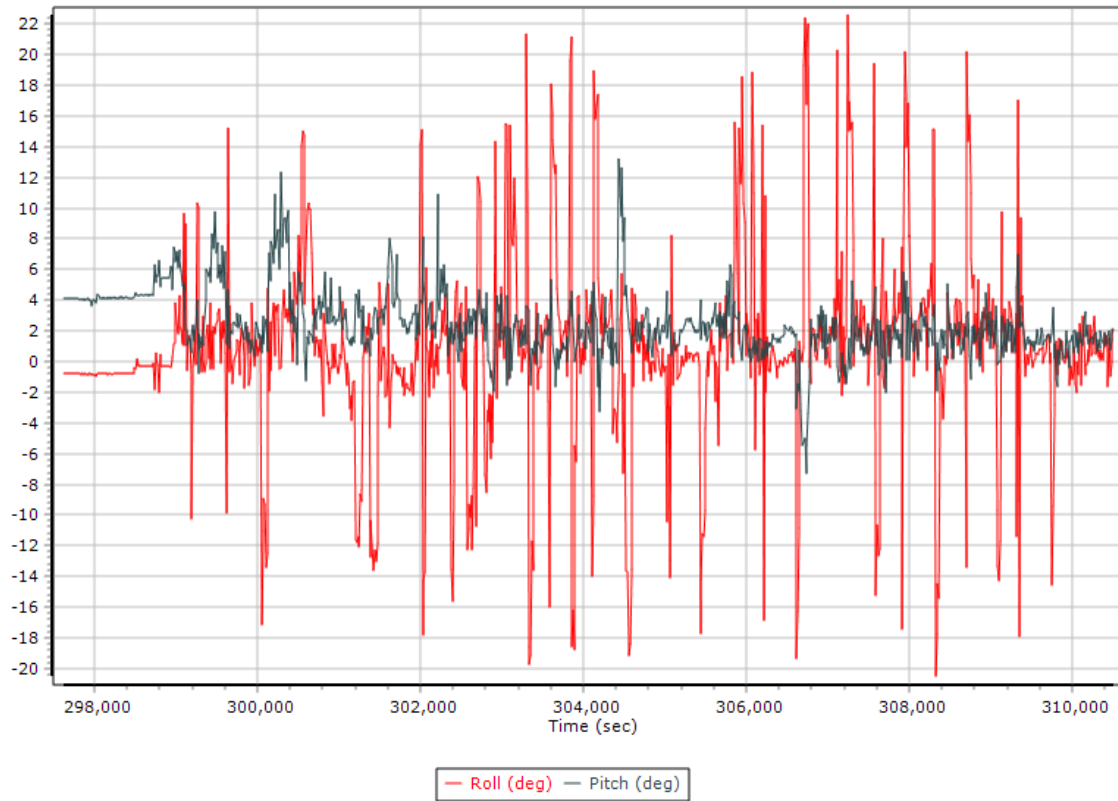
Entire time interval

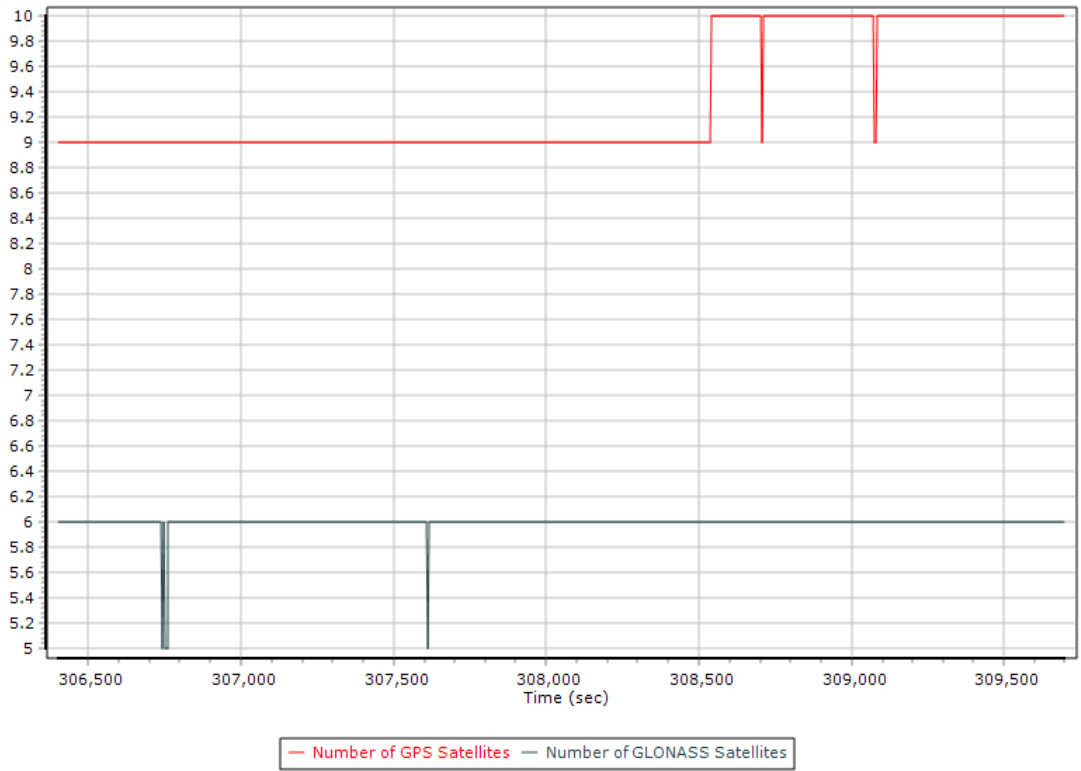
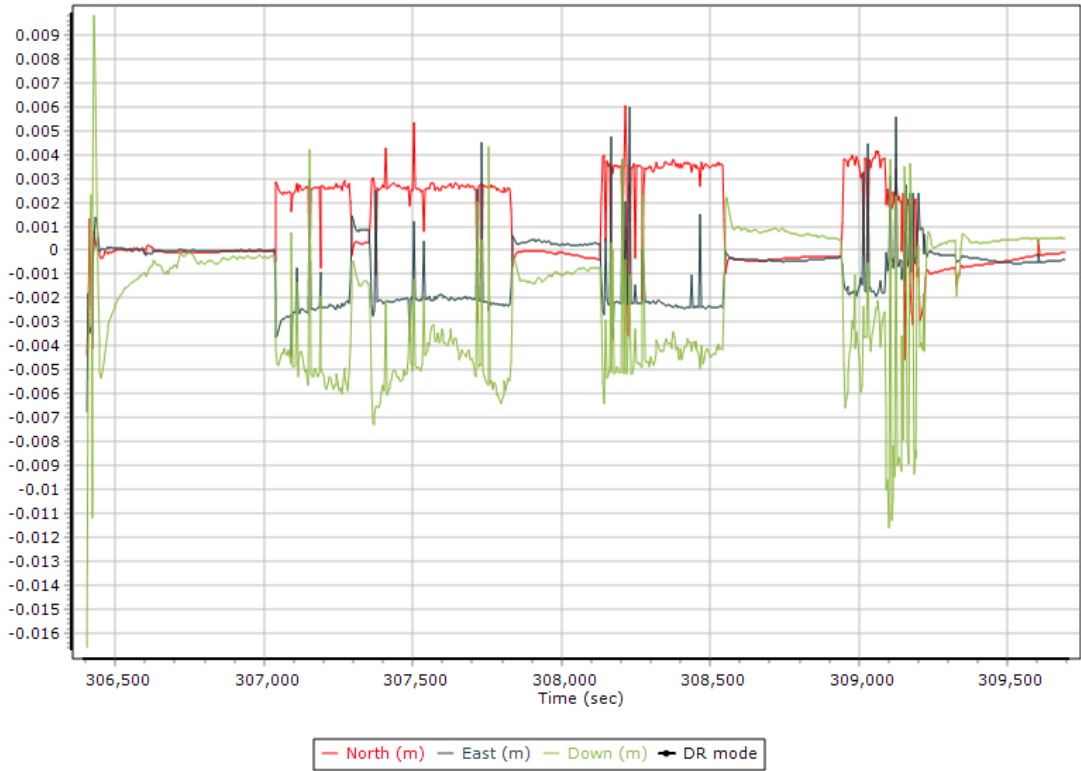
Seconds of start week

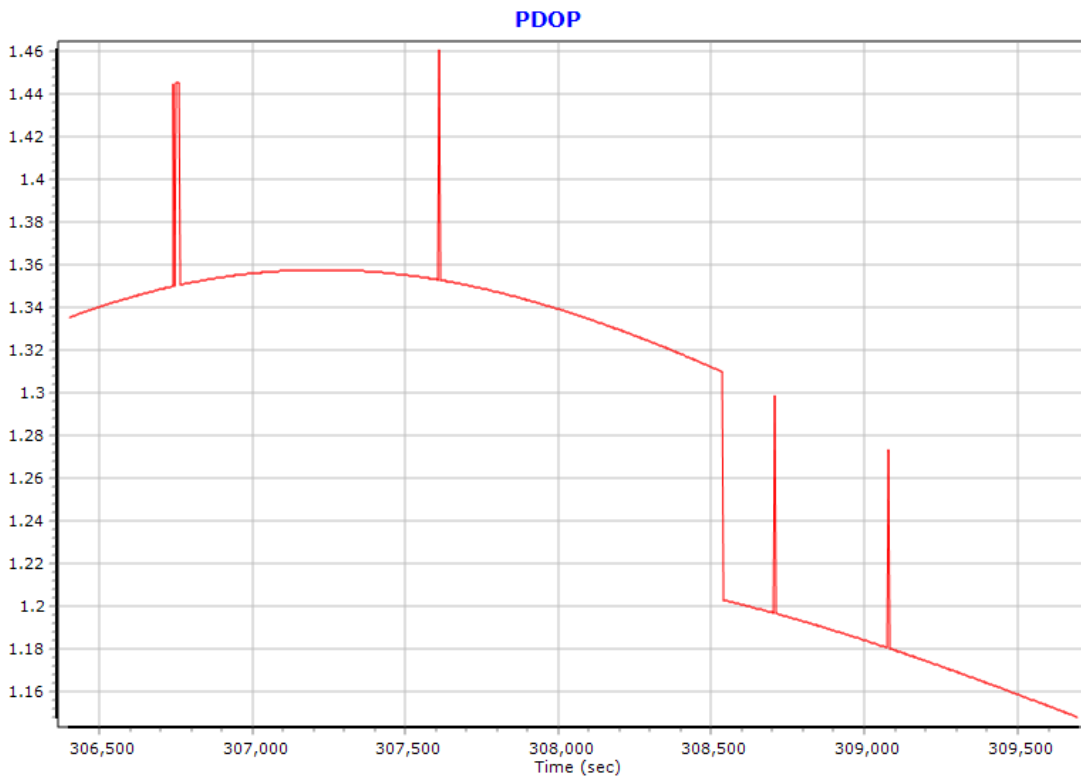
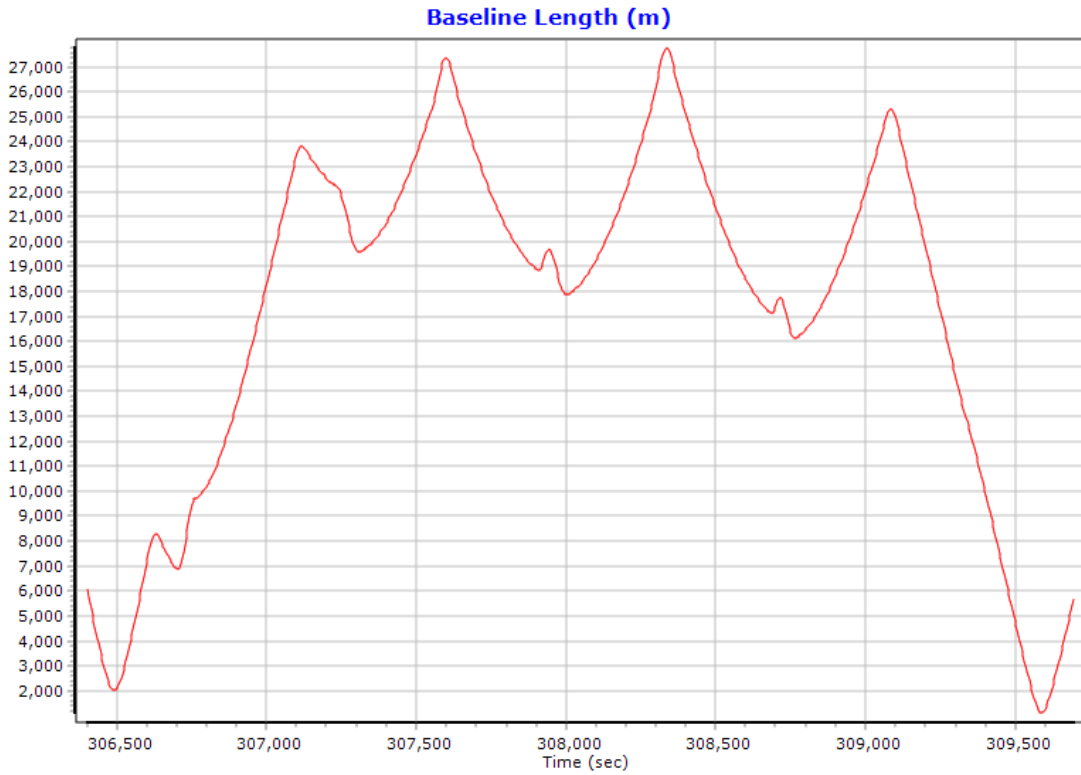
UTC Offset: 18.000

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

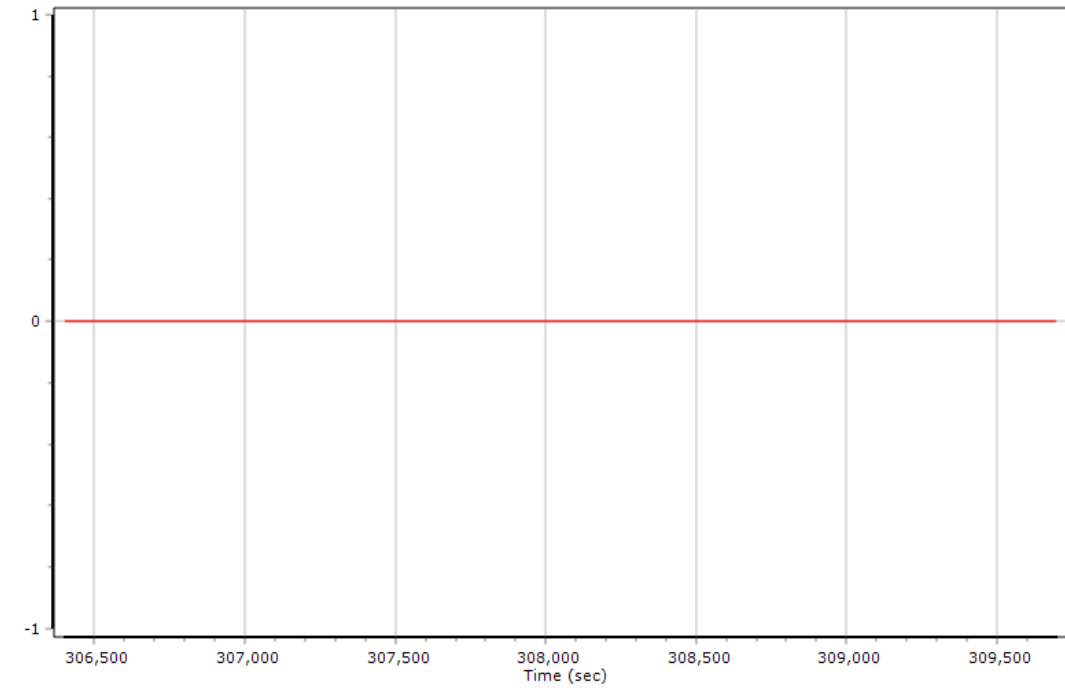






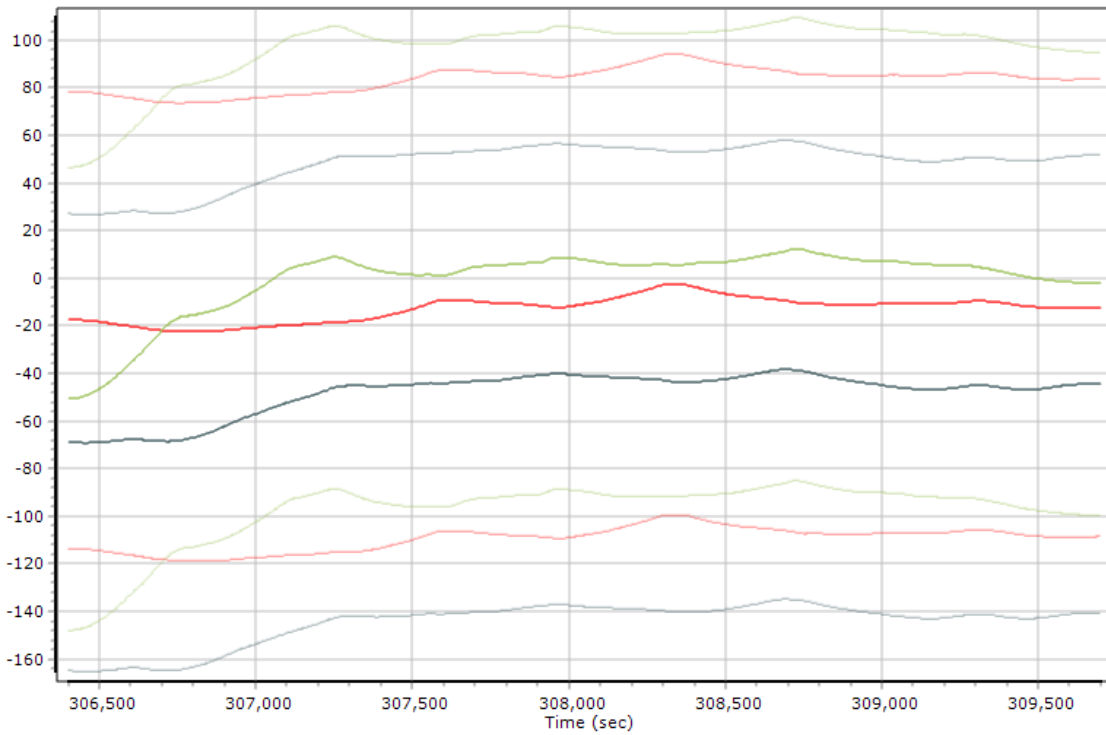


Processing mode

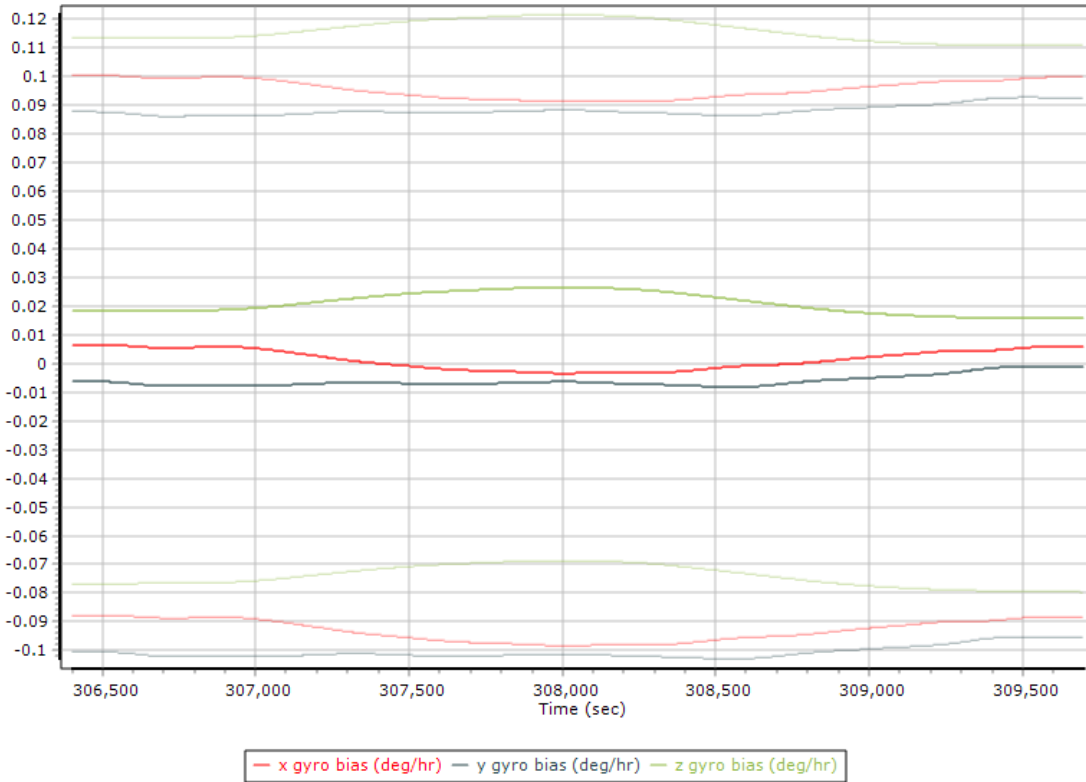
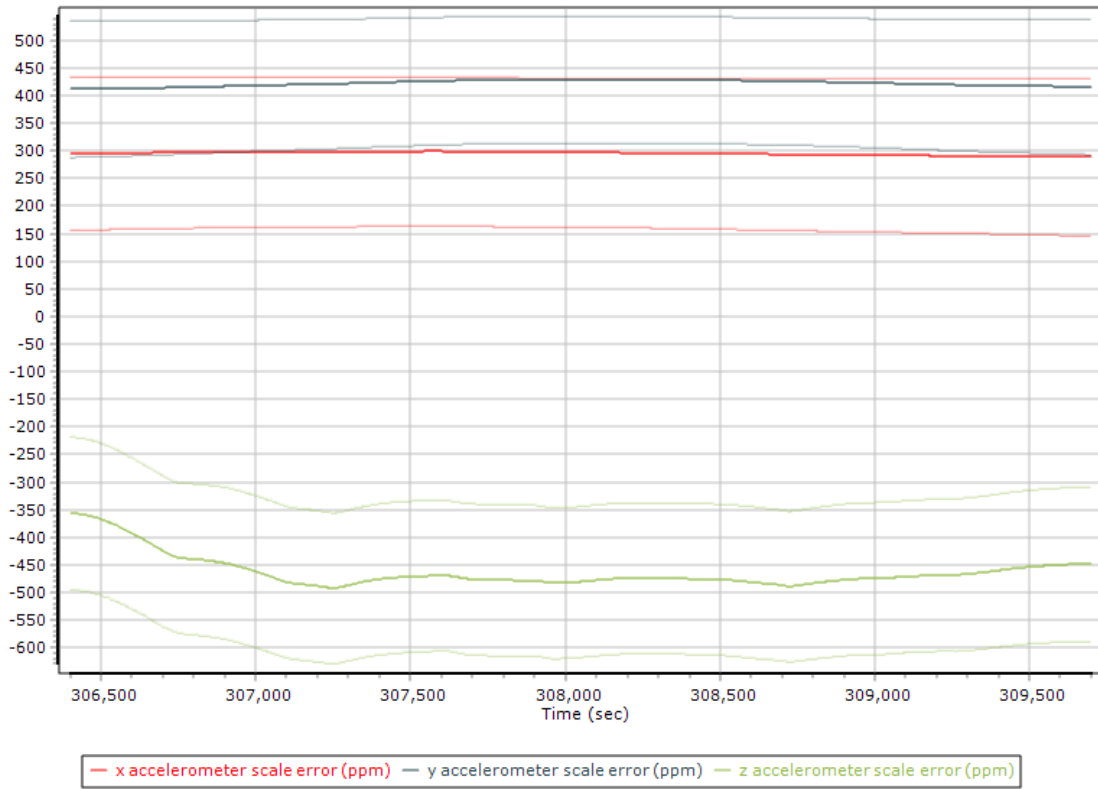


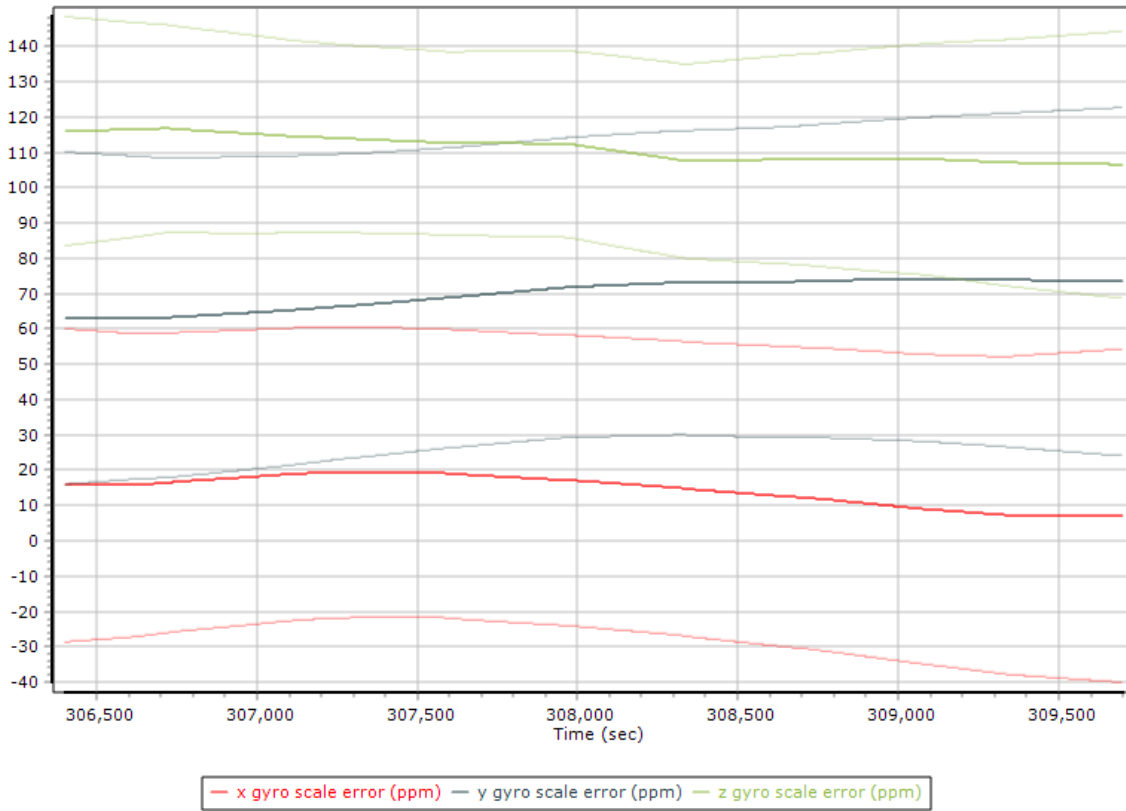
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

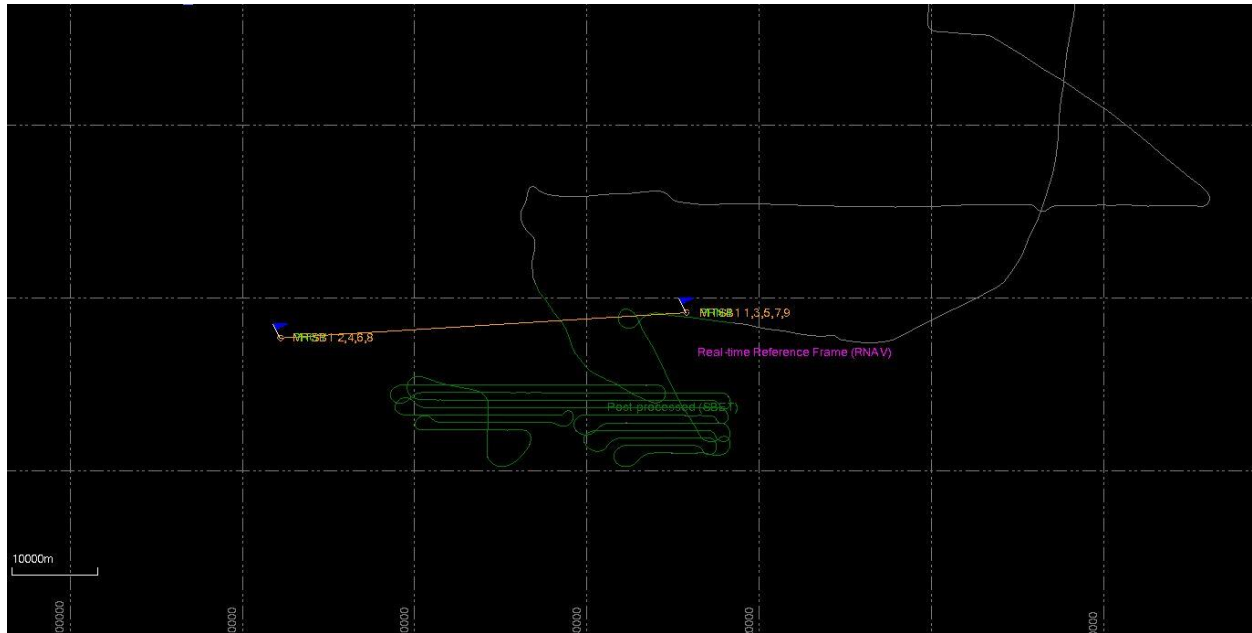


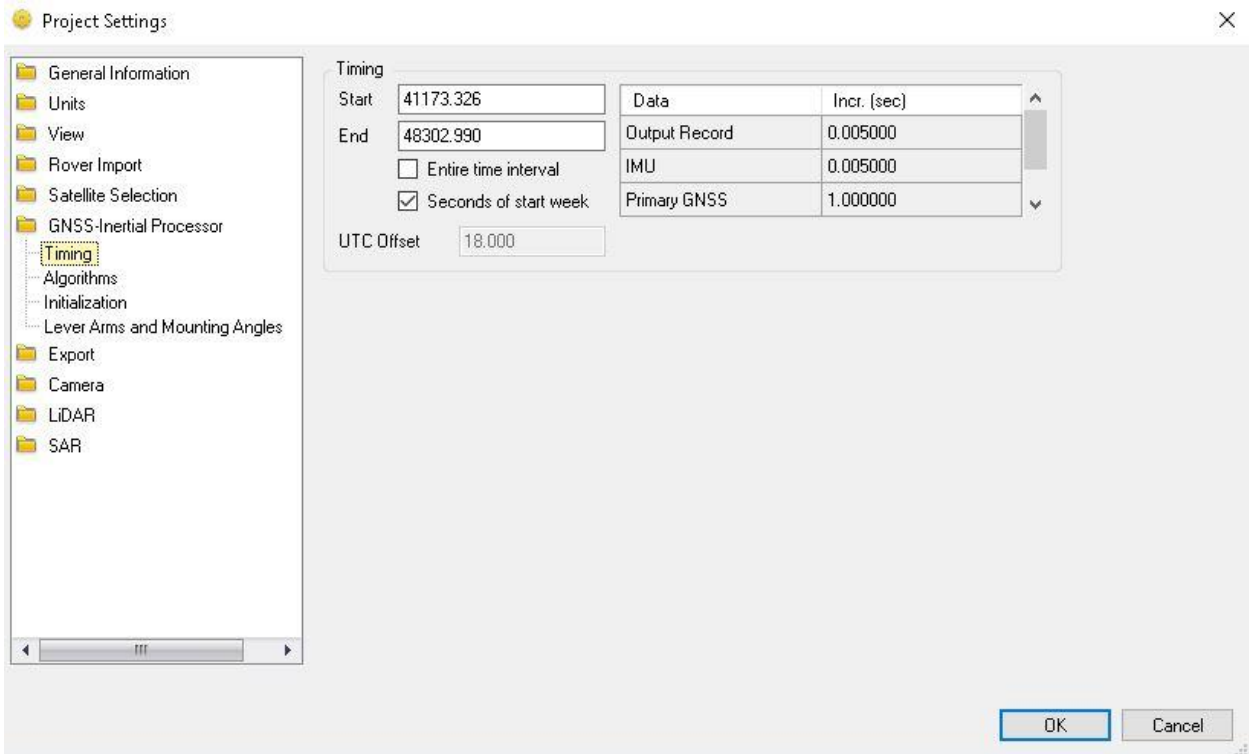
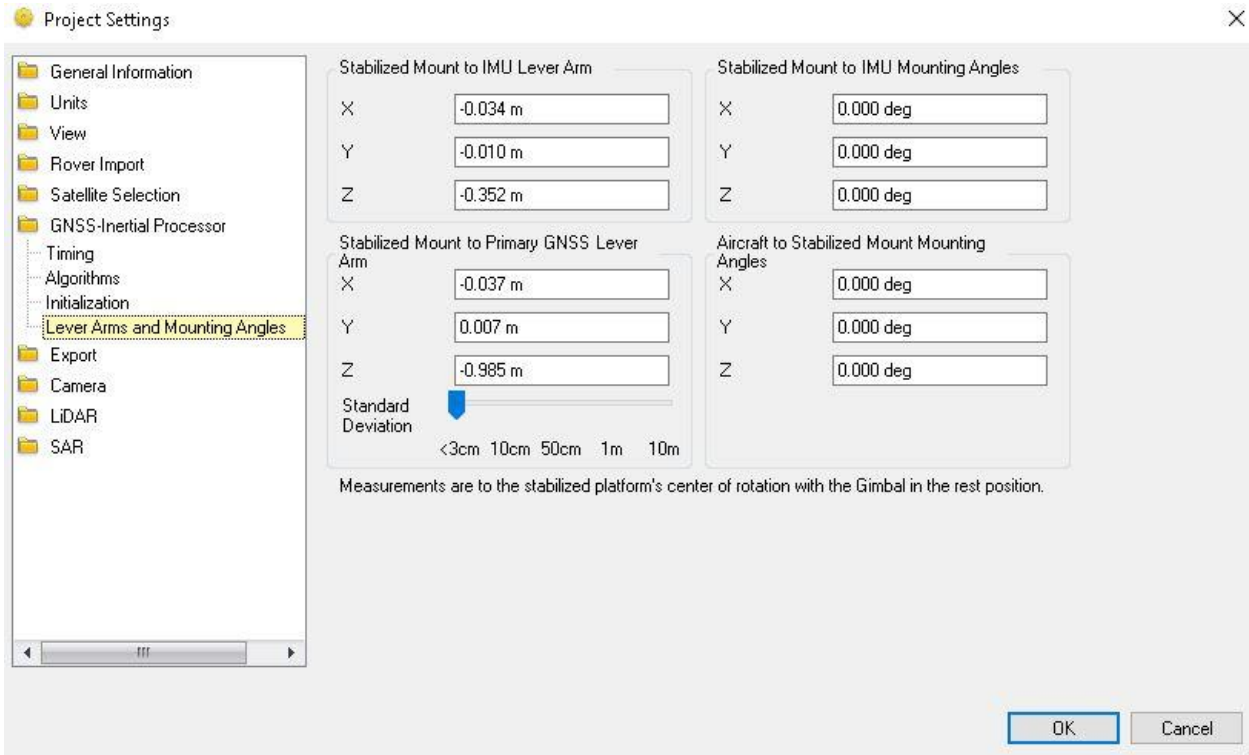
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



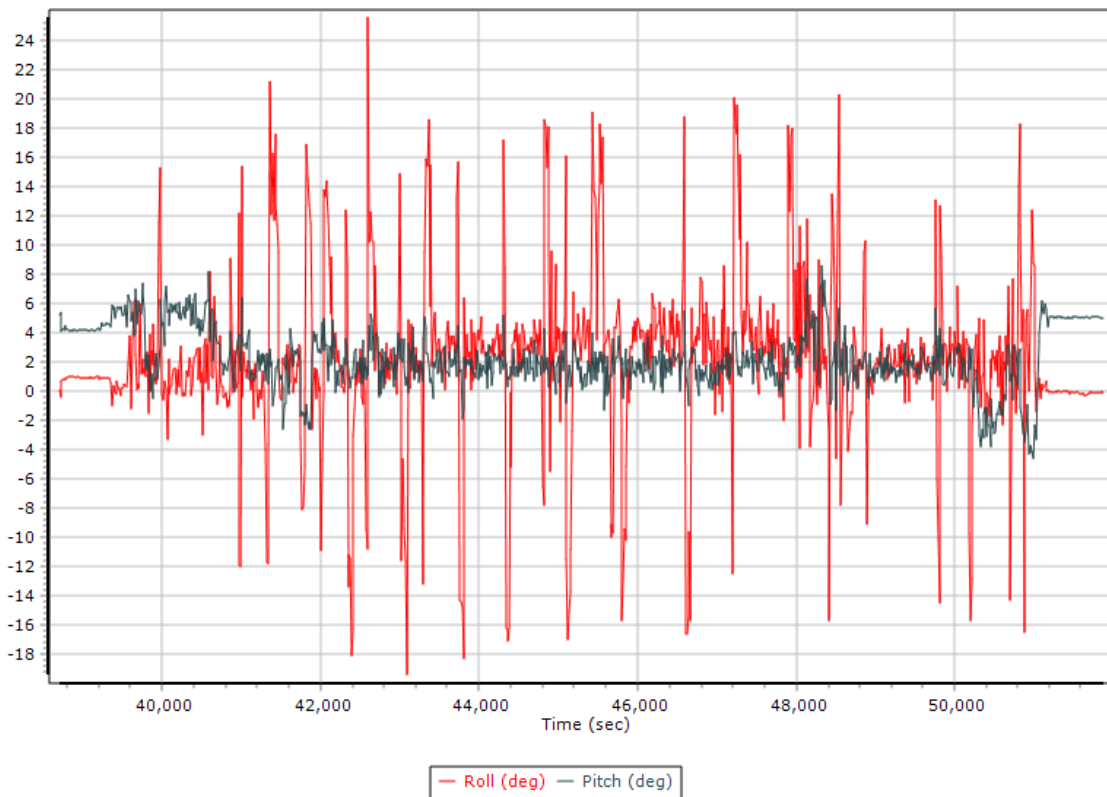
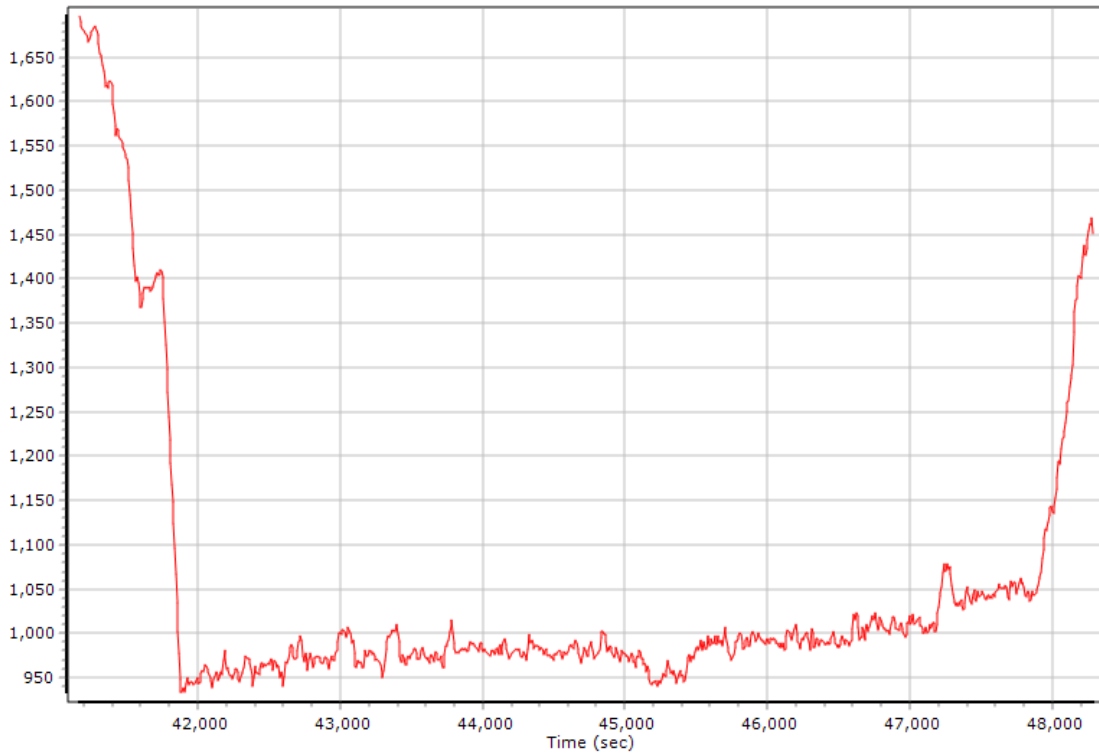


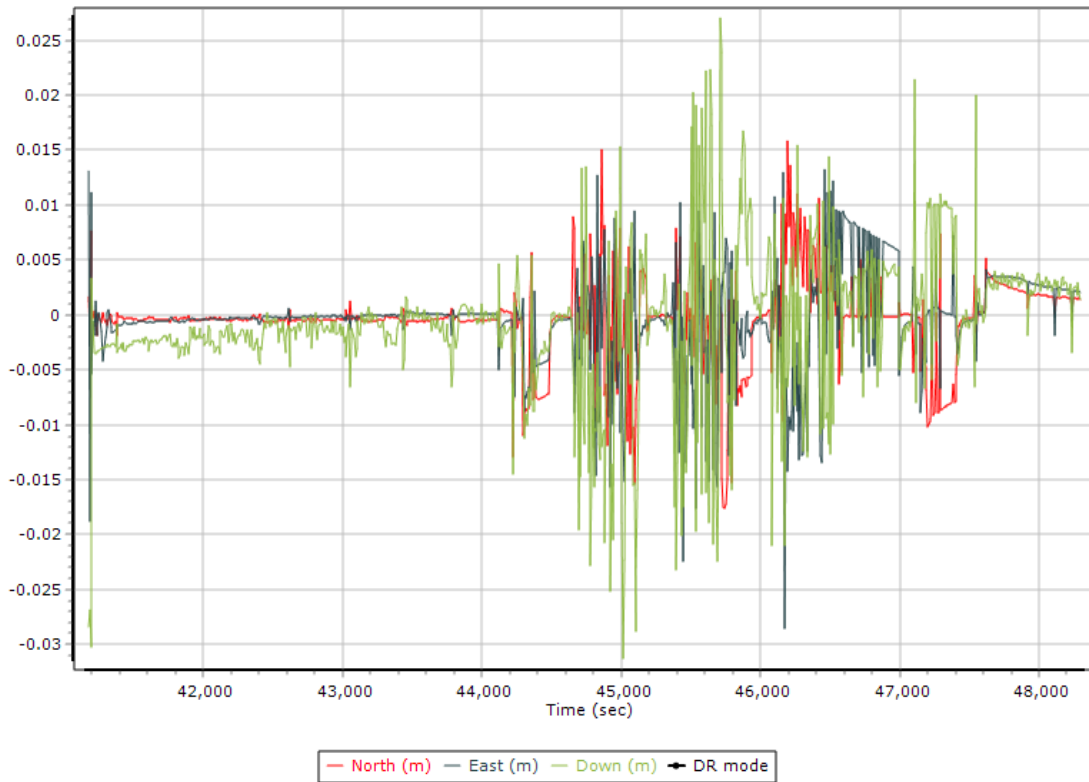
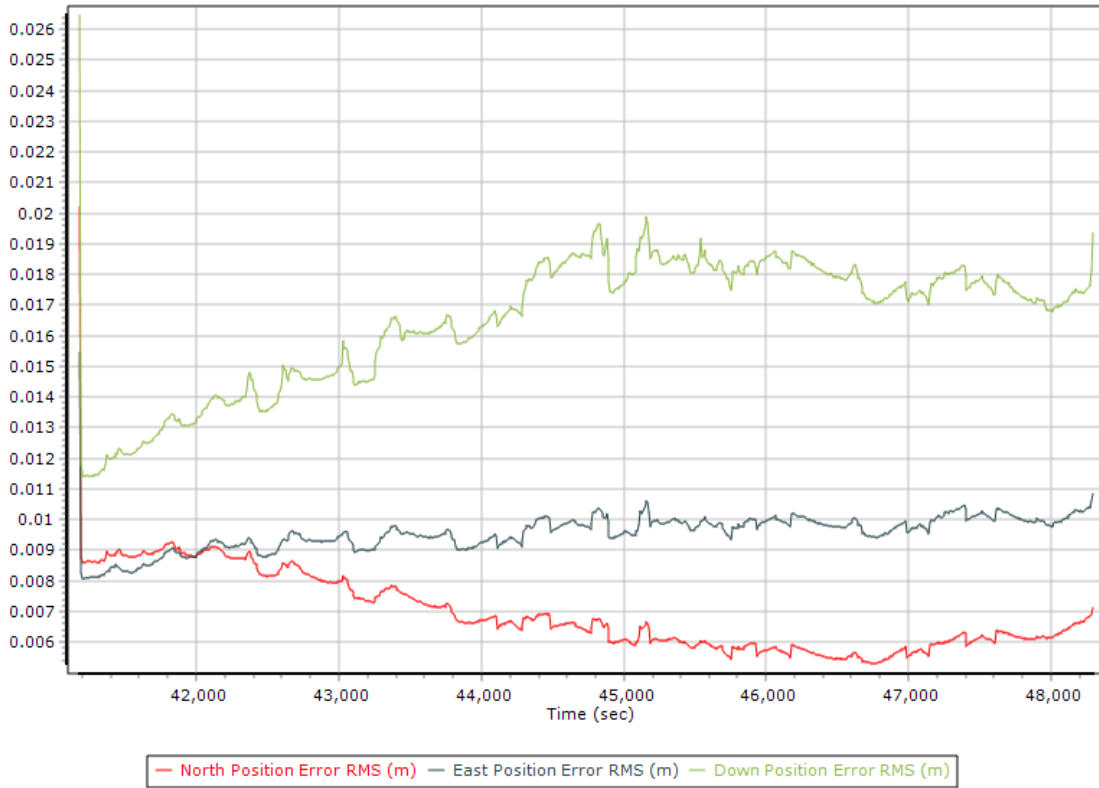
RBV18108B

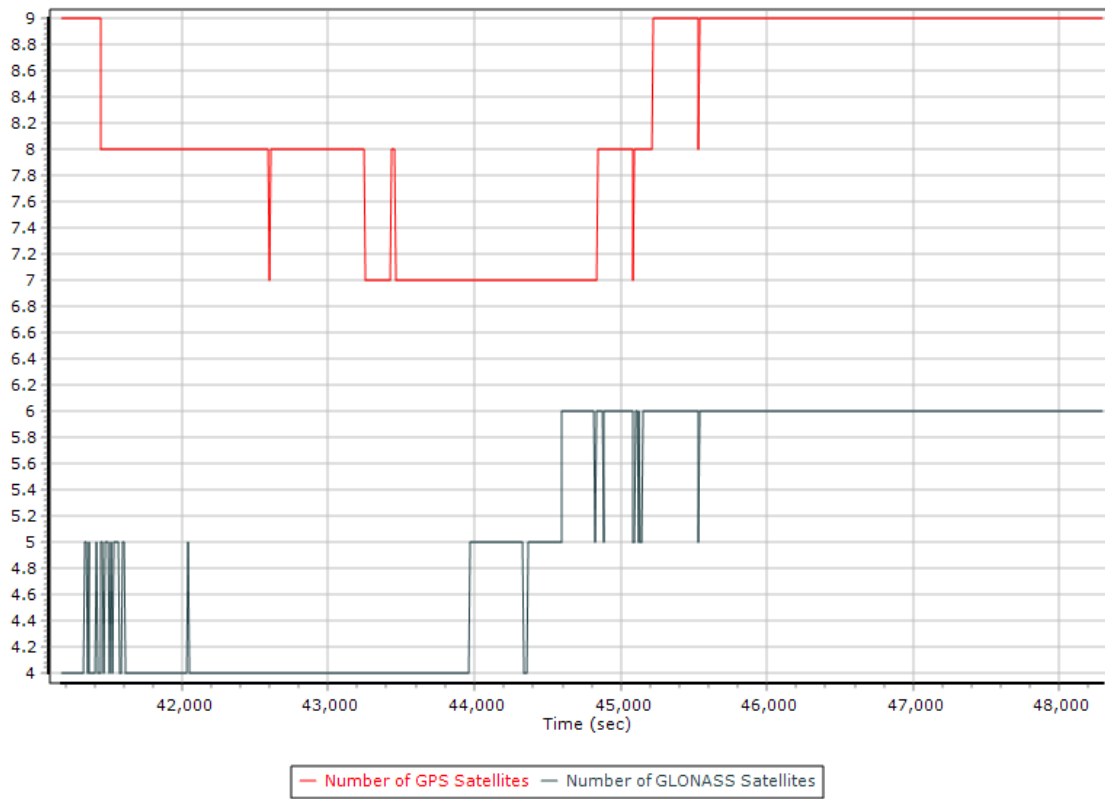




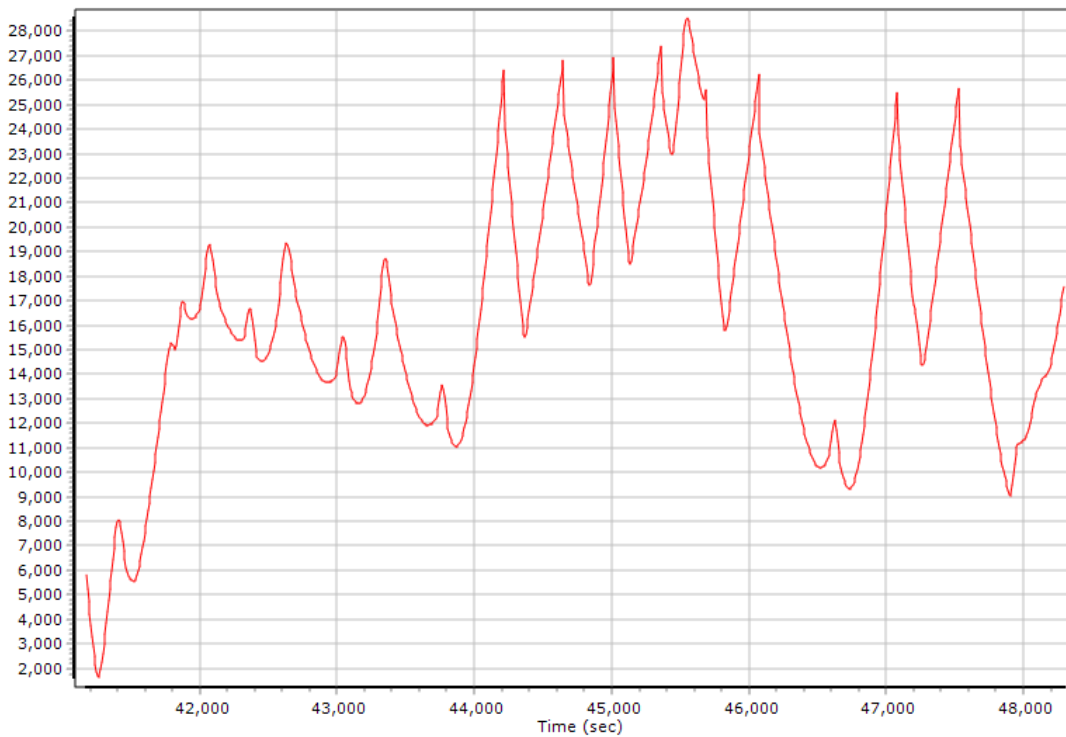
Altitude (m)

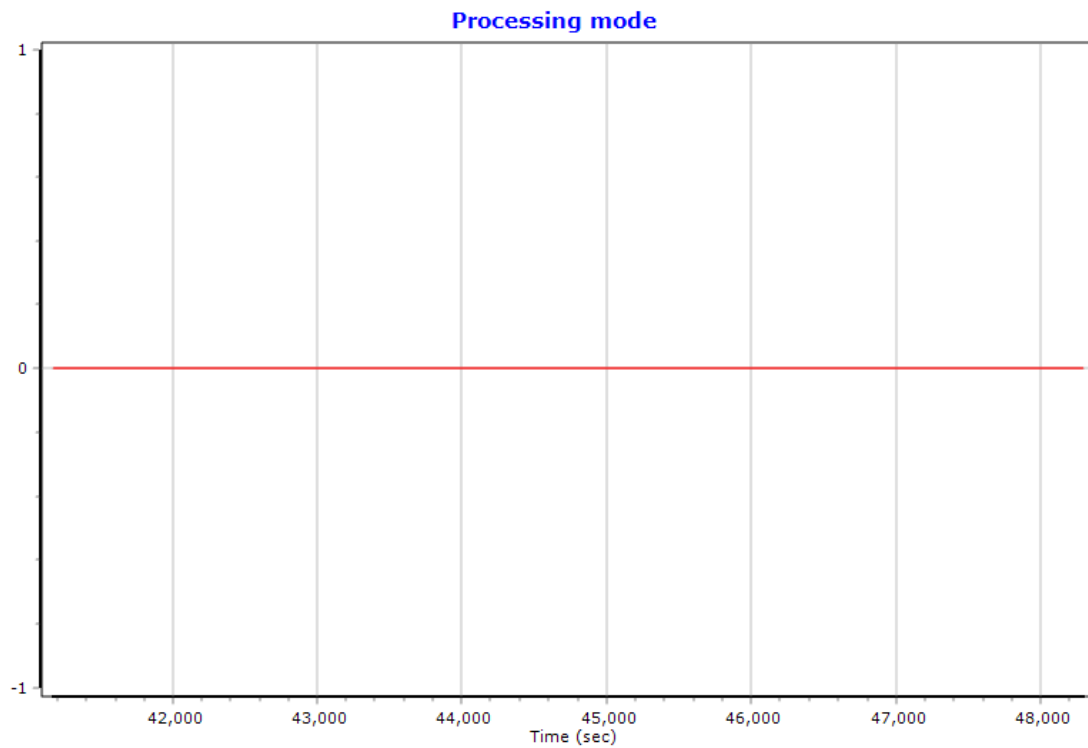
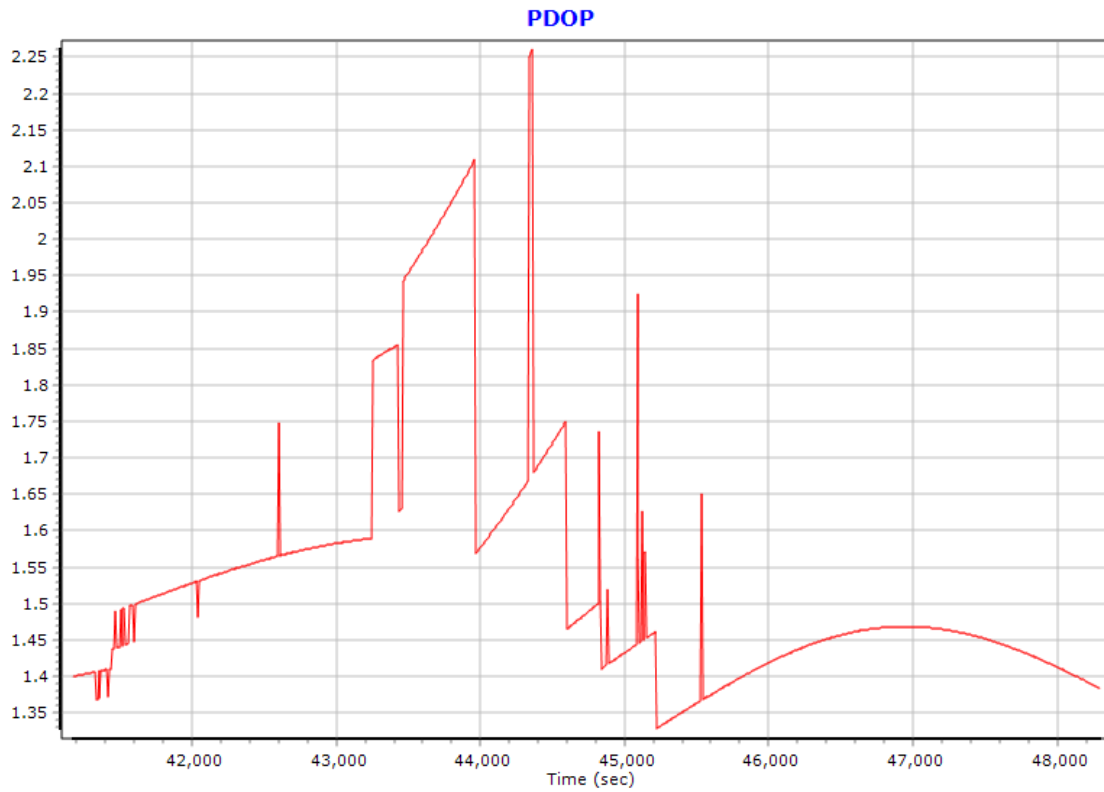






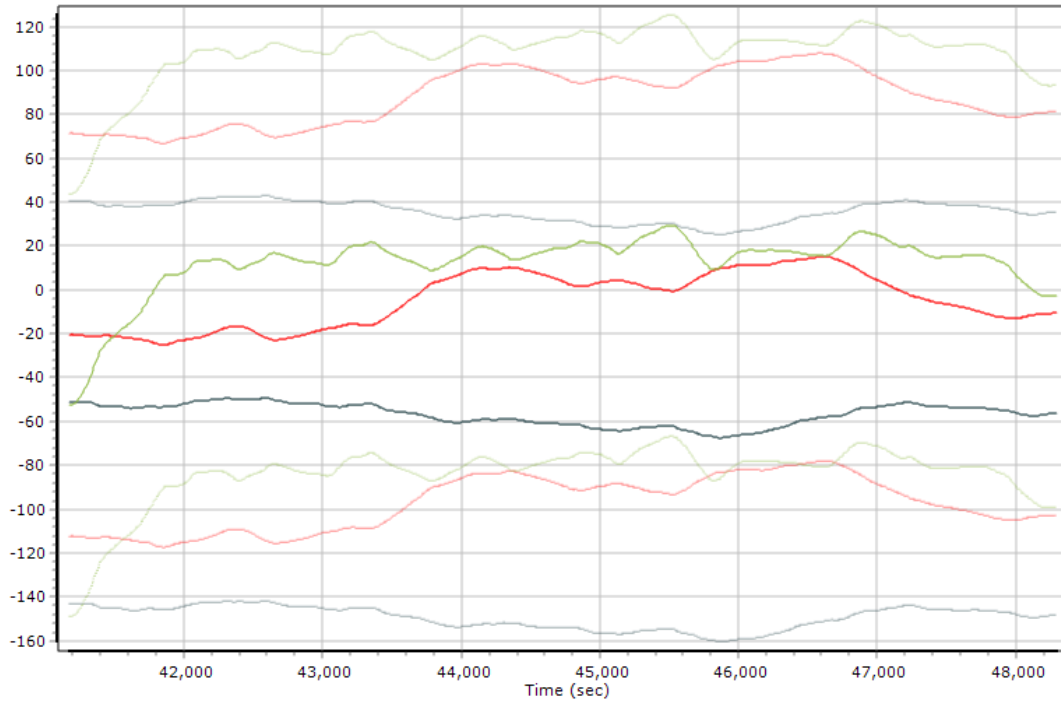
Baseline Length (m)



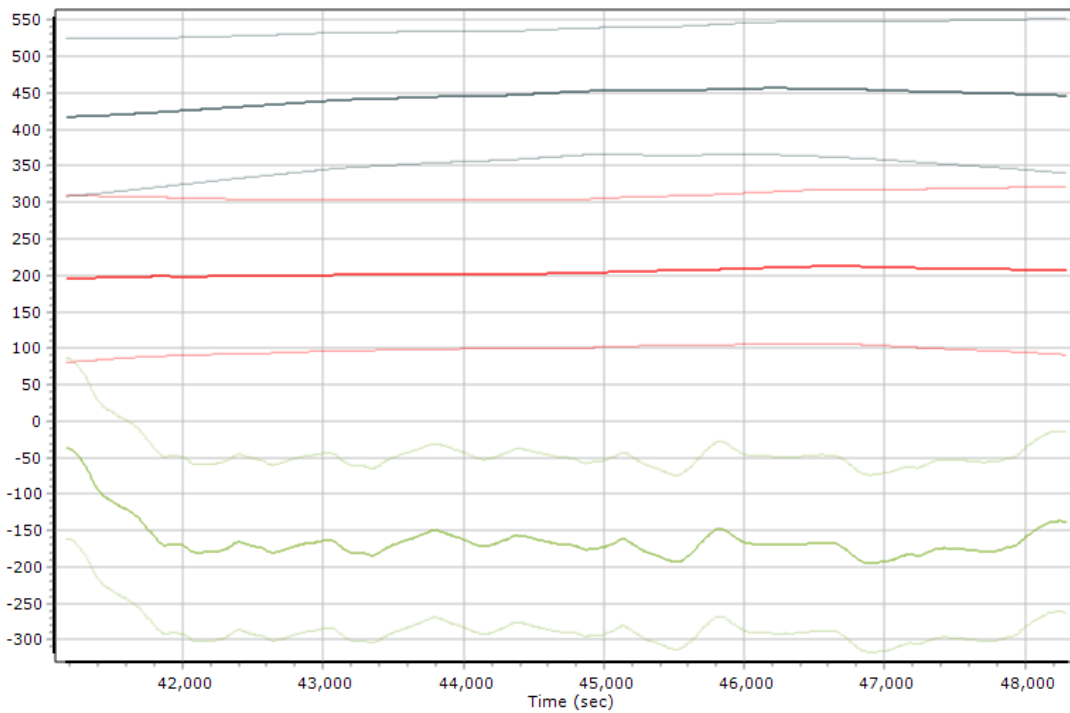


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

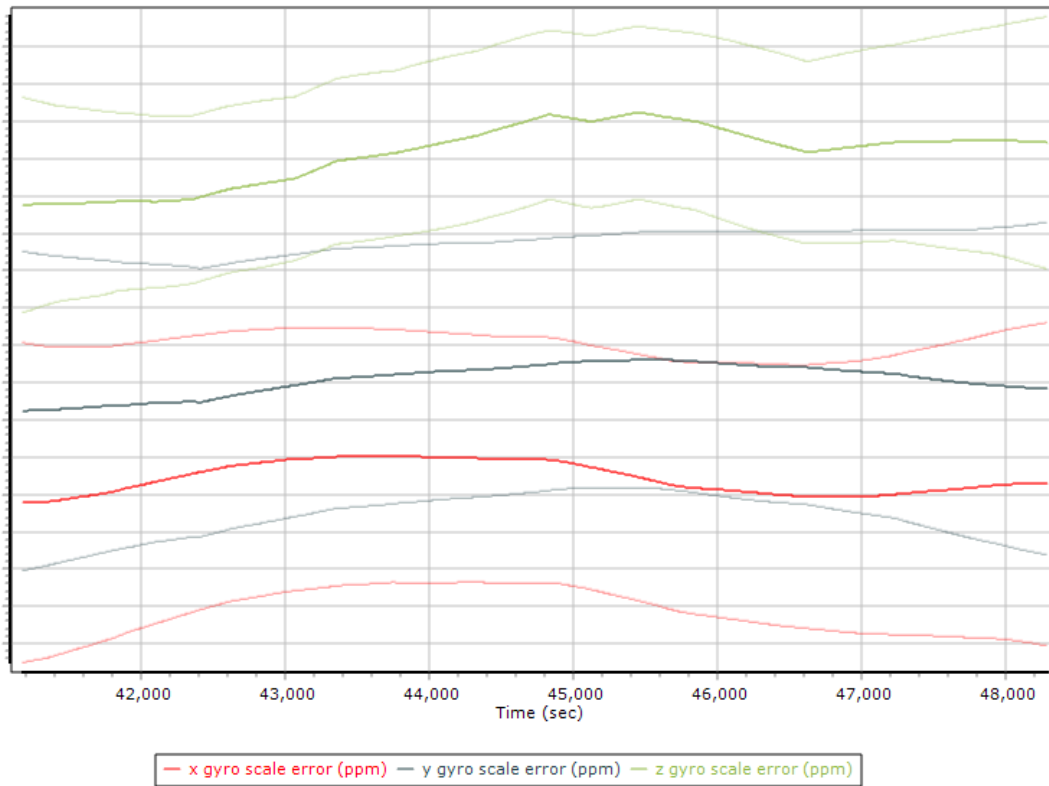
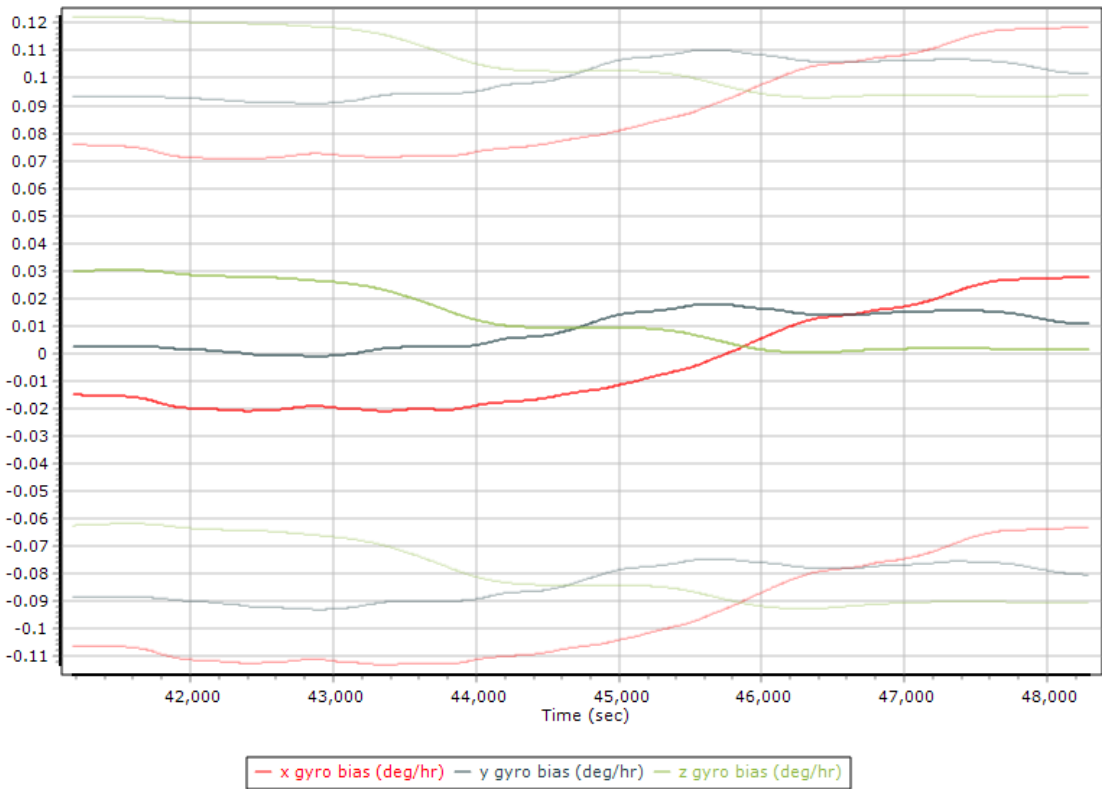
Sensor Errors



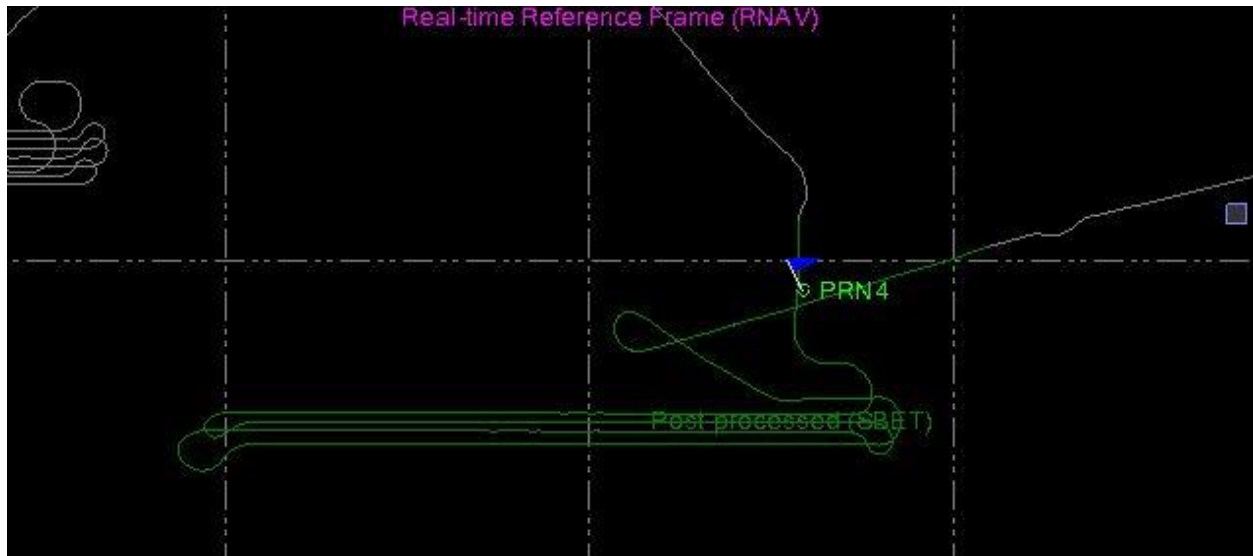
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)



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



RBV18113A1



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

Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.037 m	0.007 m	-0.985 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	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

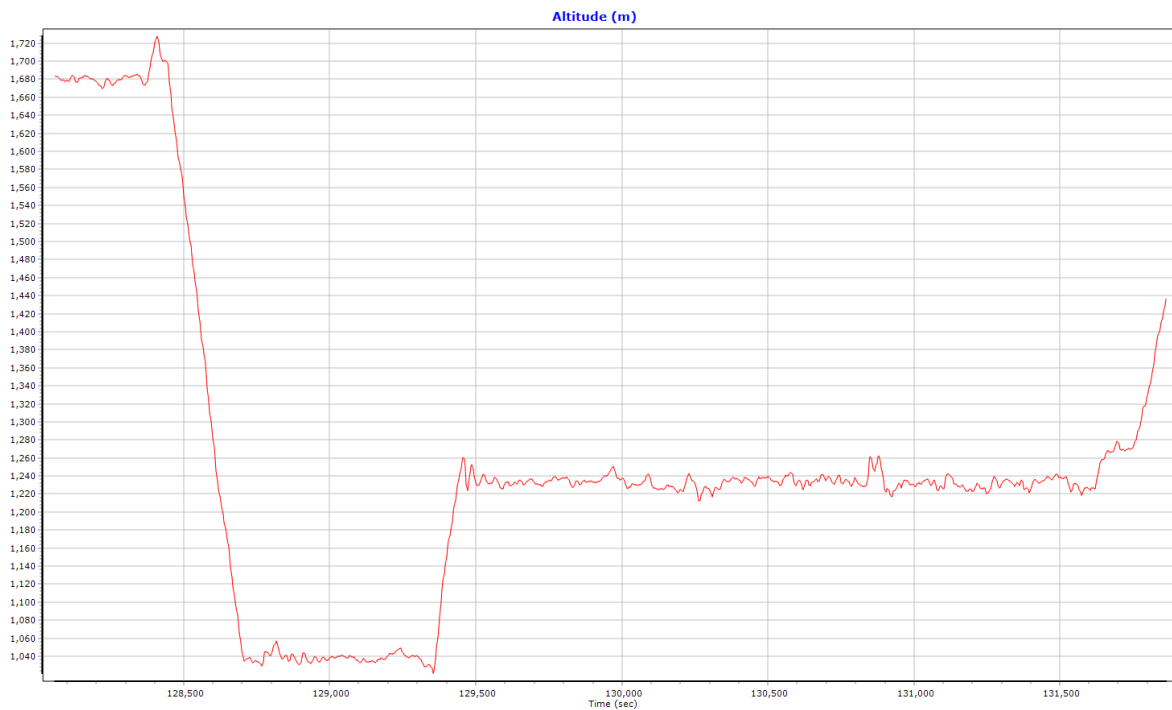
Project Settings

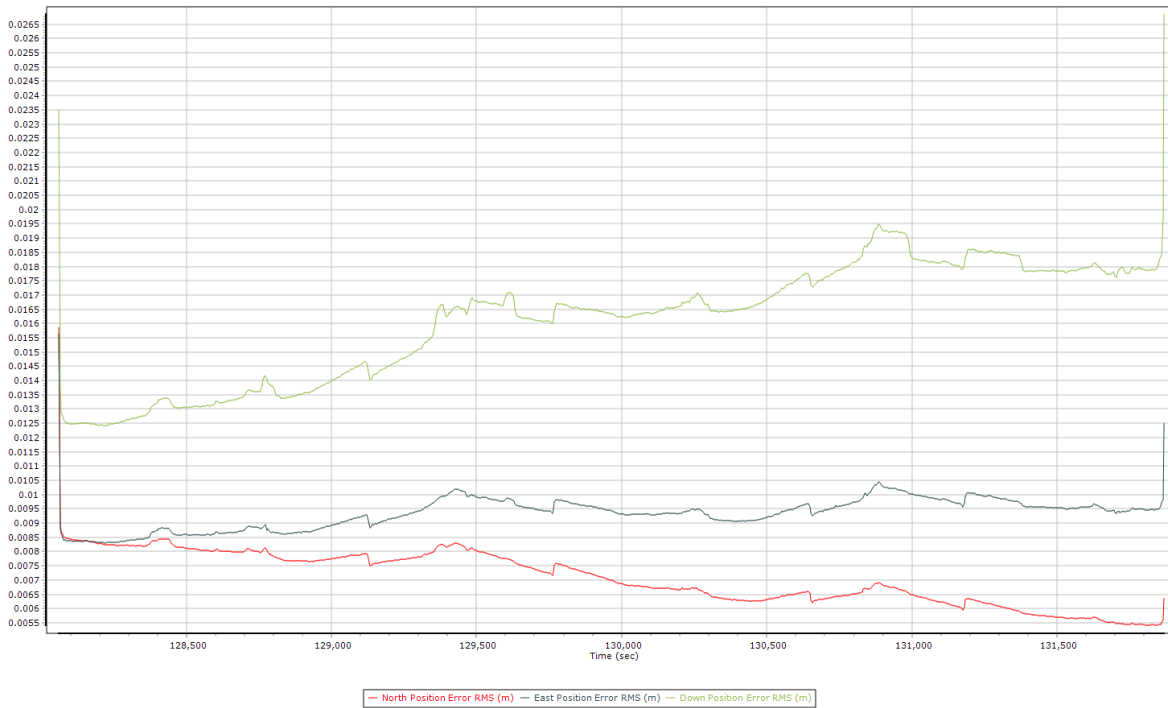
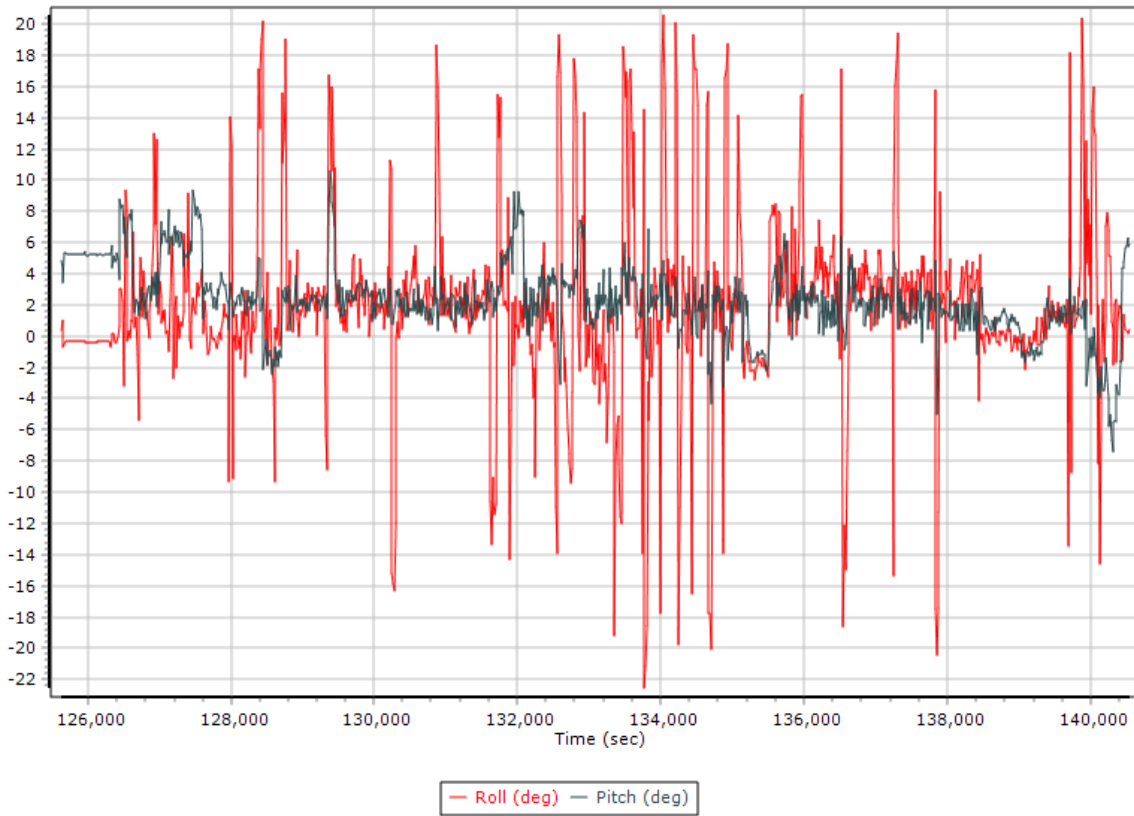
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
Timing
Algorithms
Initialization
Lever Arms and Mounting Angles
Export
Camera
LiDAR
SAR

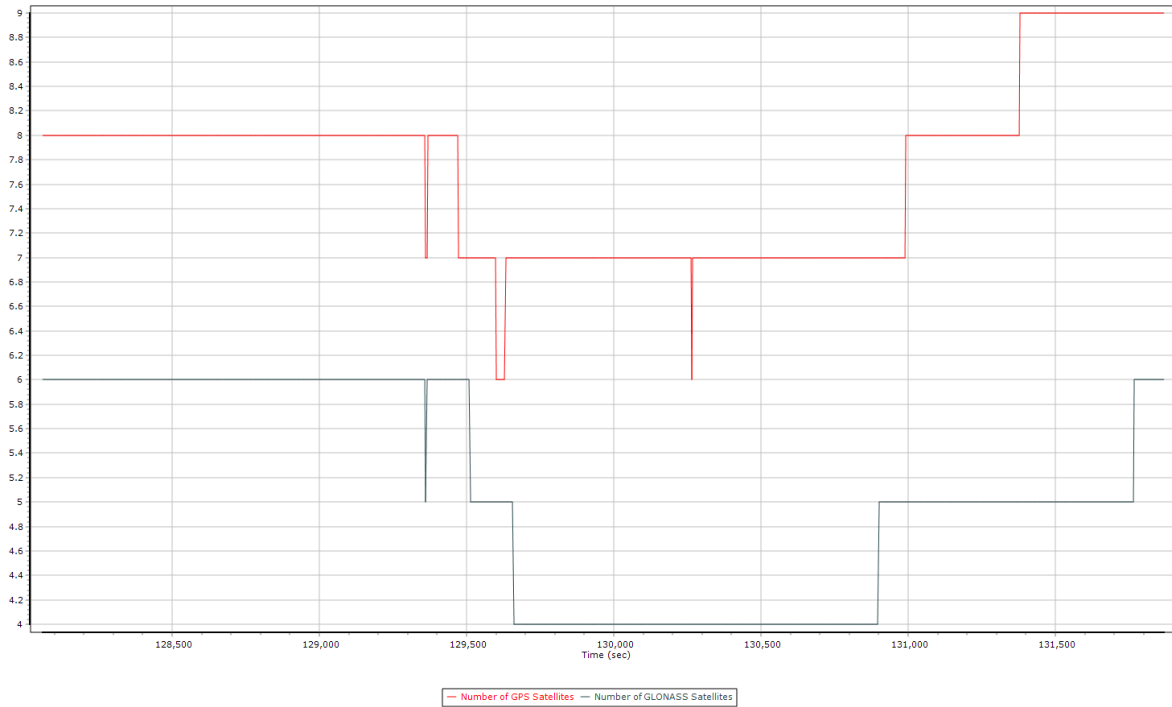
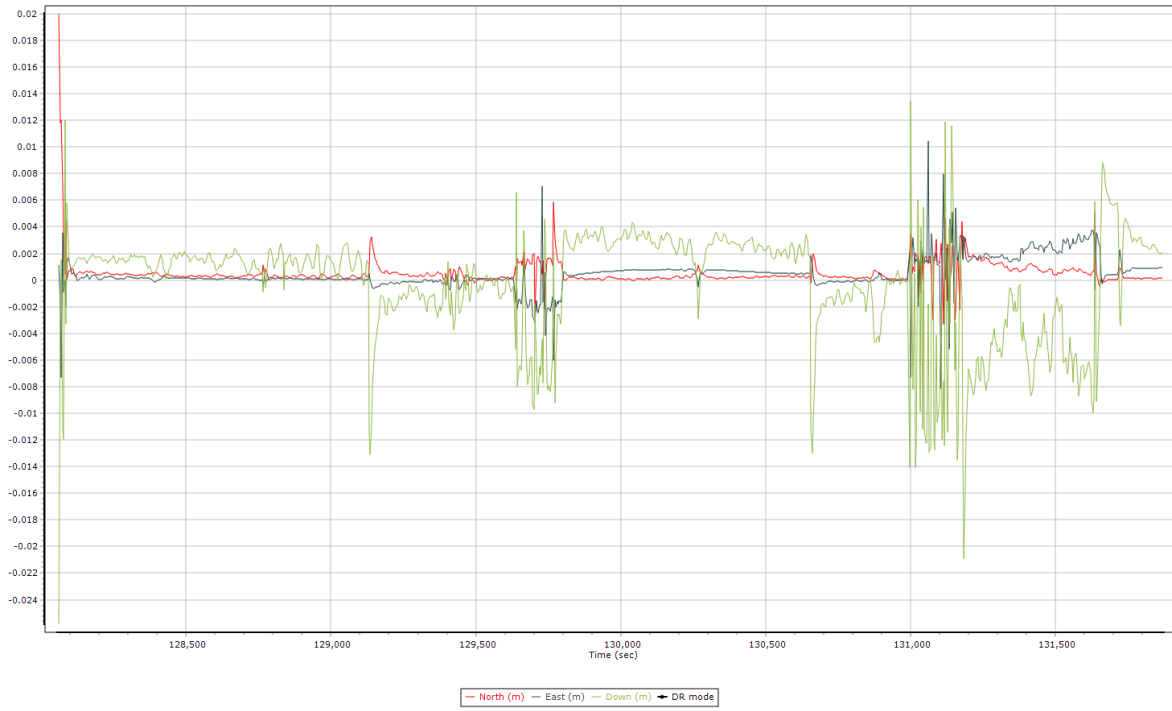
Timing
Start: 128058.065
End: 131871.953
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

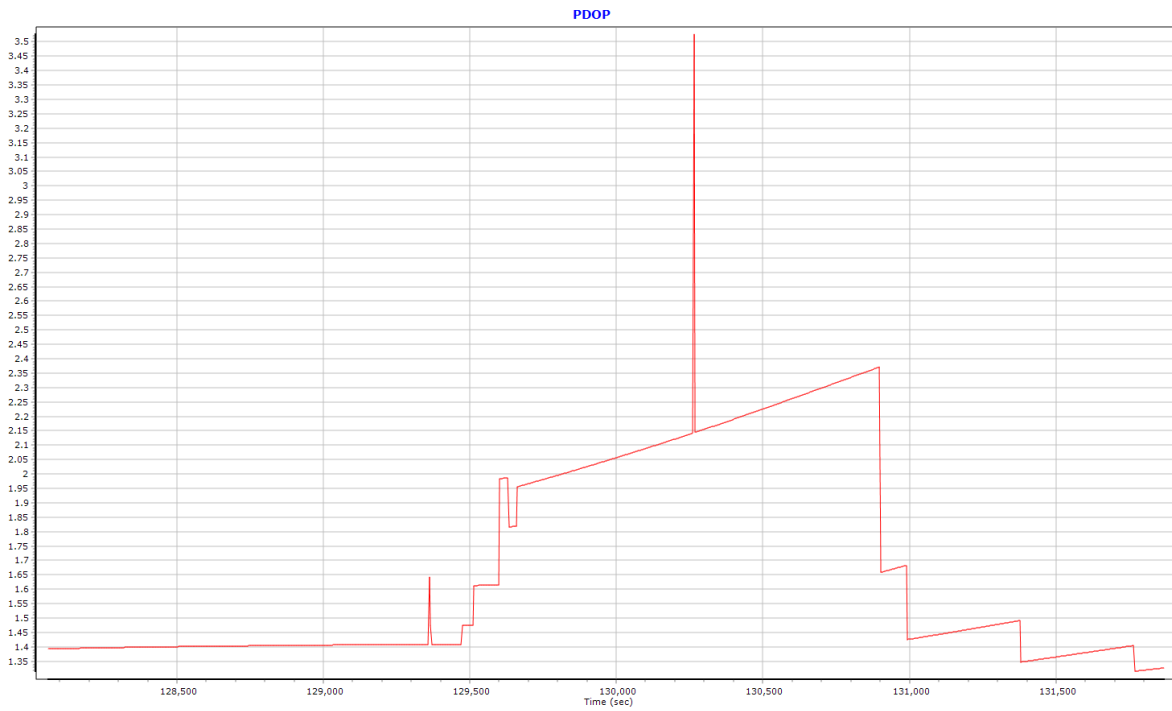
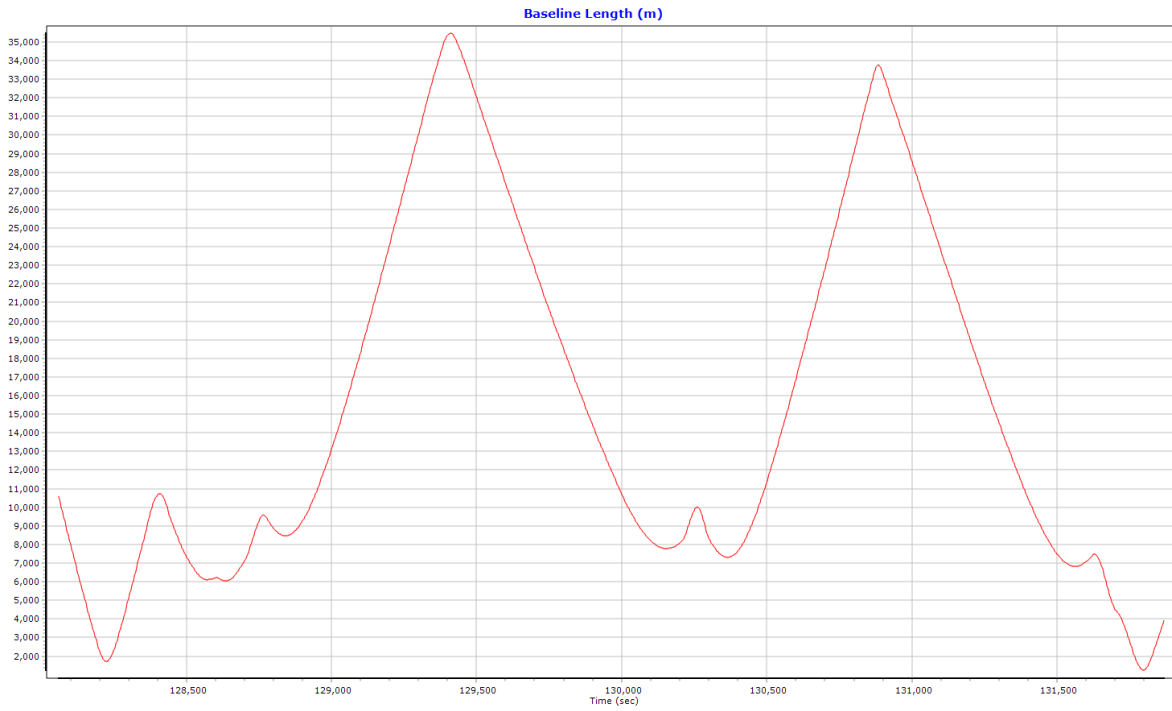
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

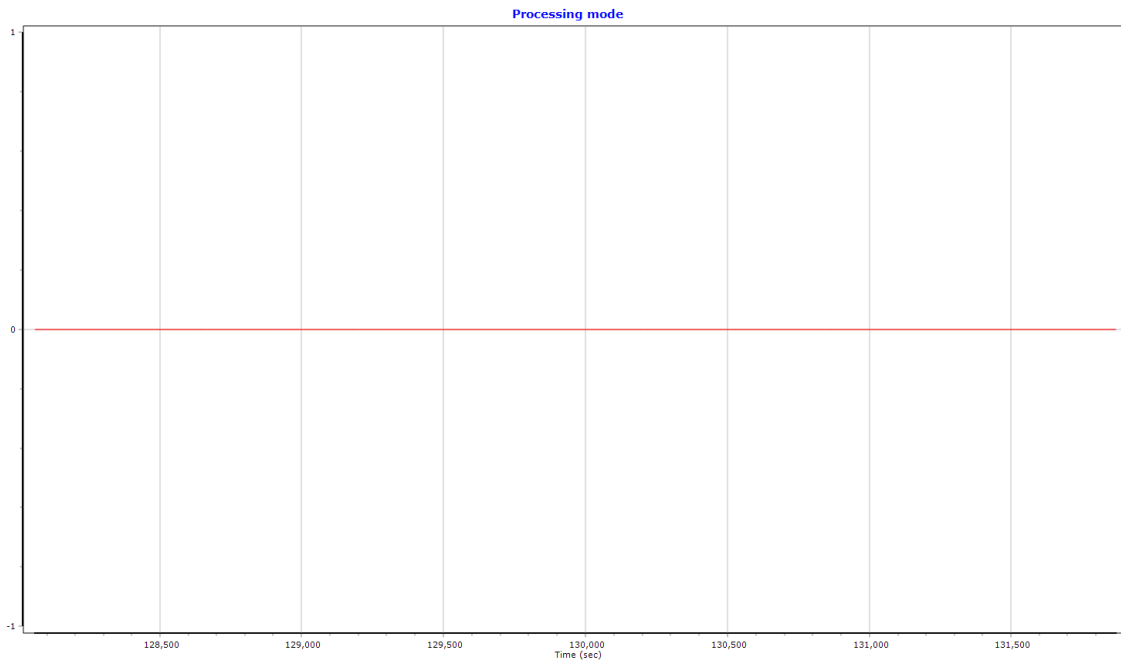
OK Cancel



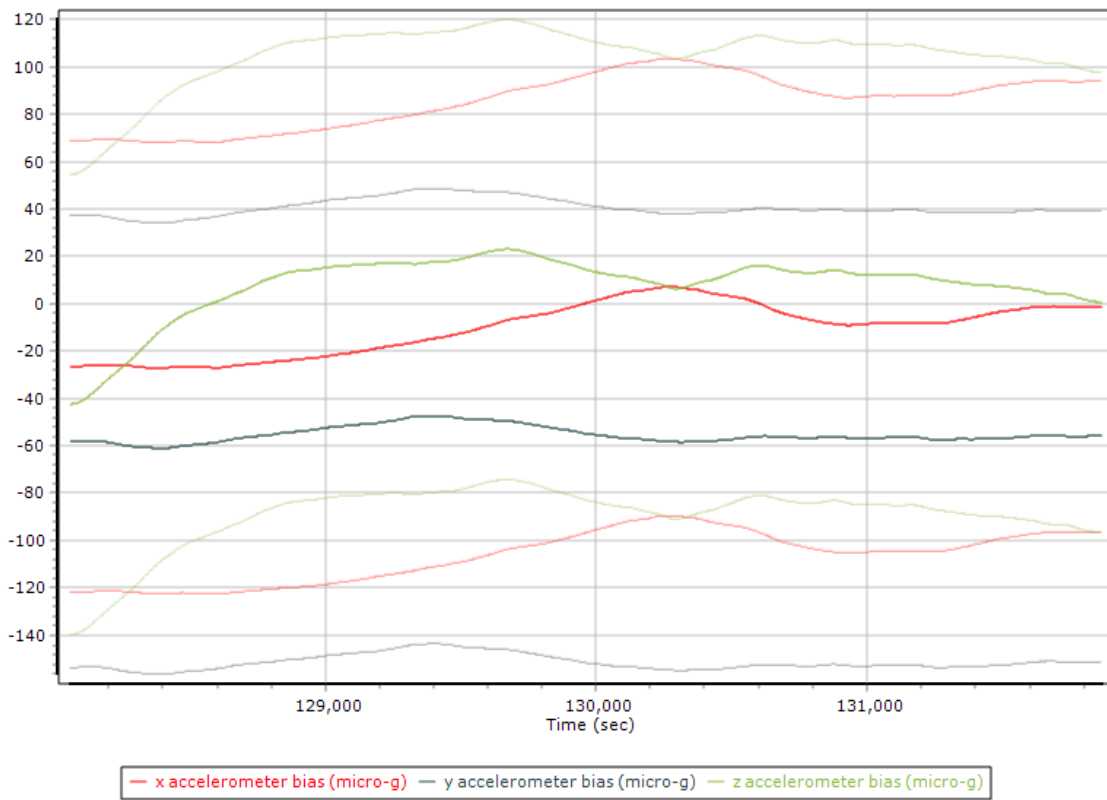


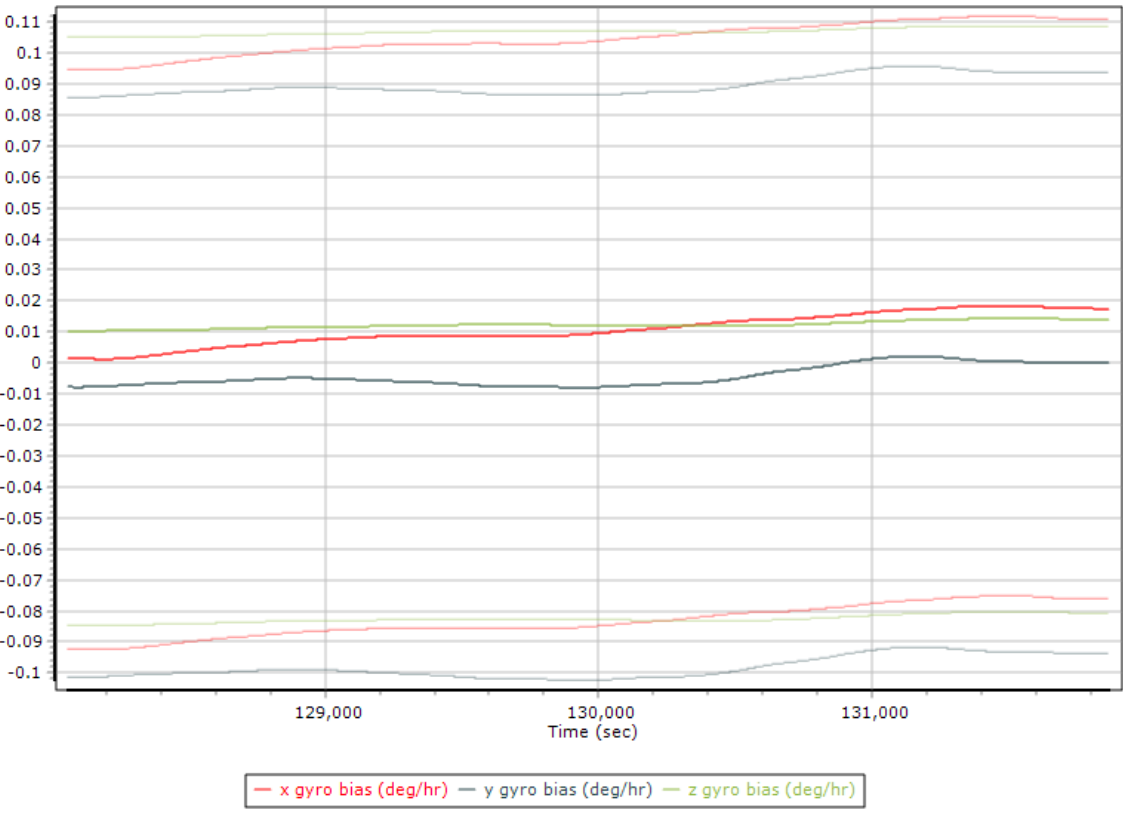
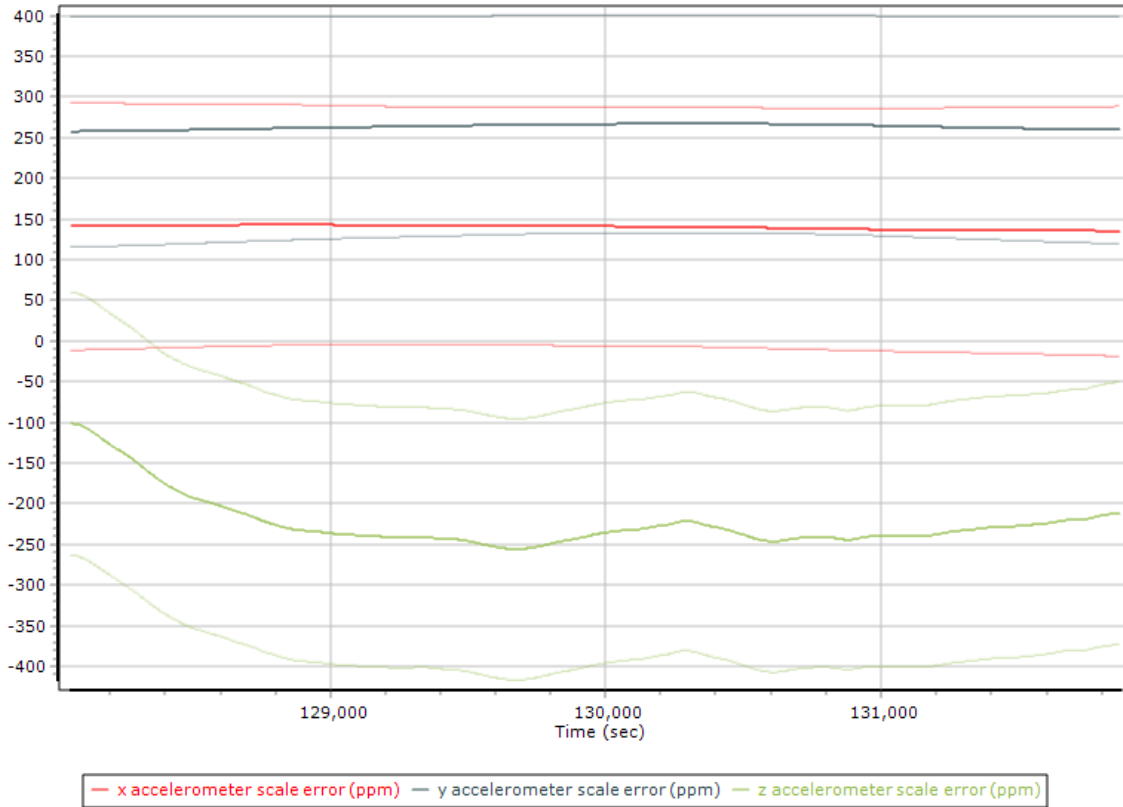






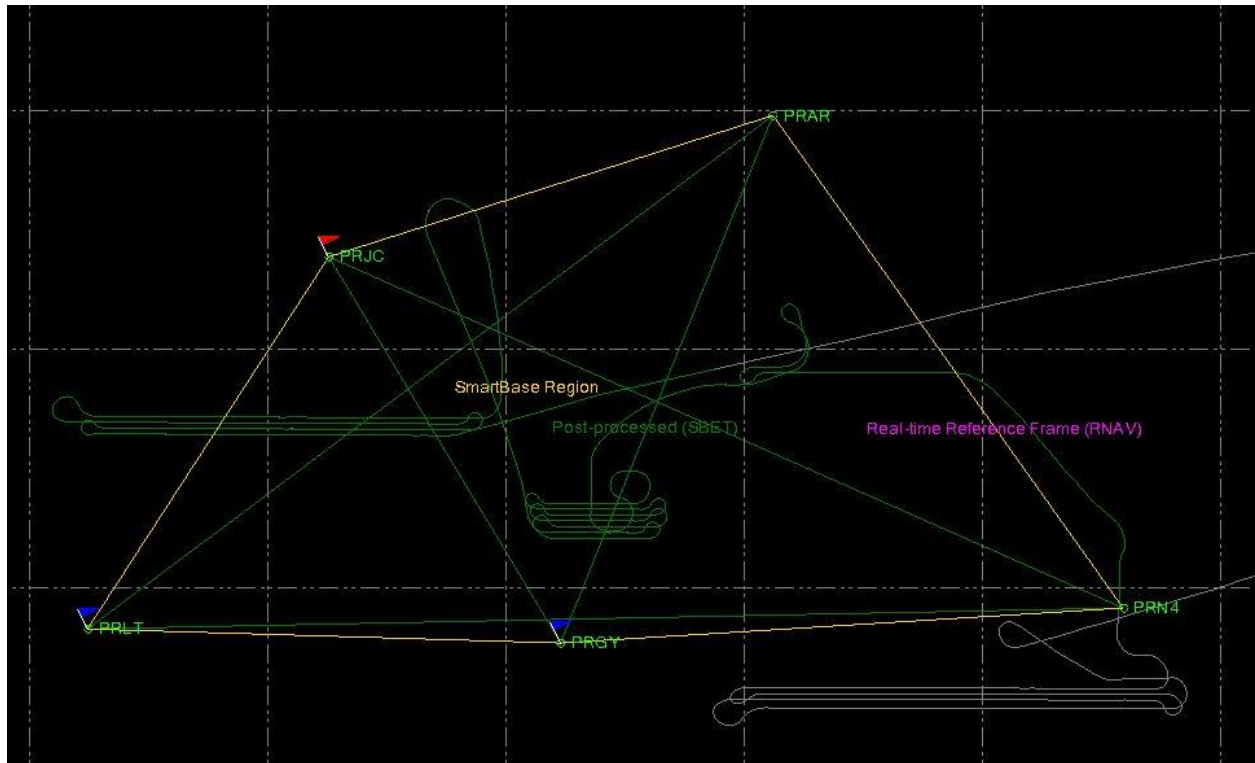
Sensor Errors

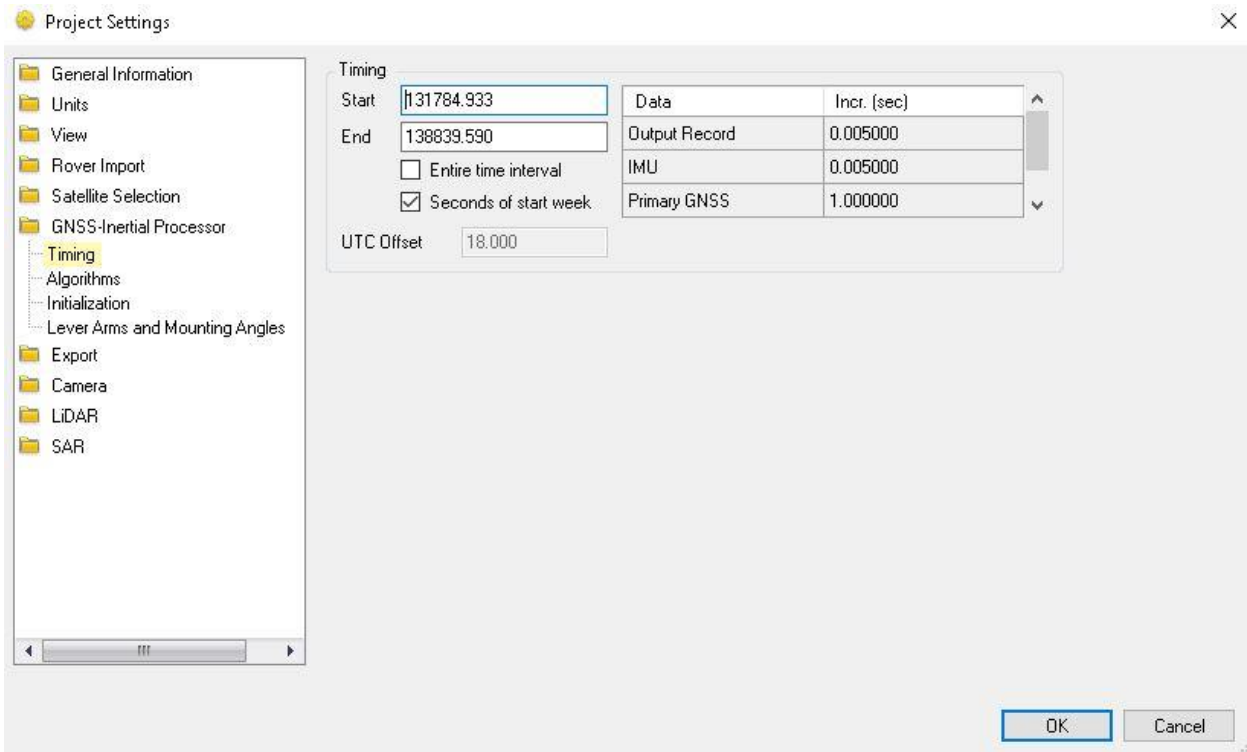
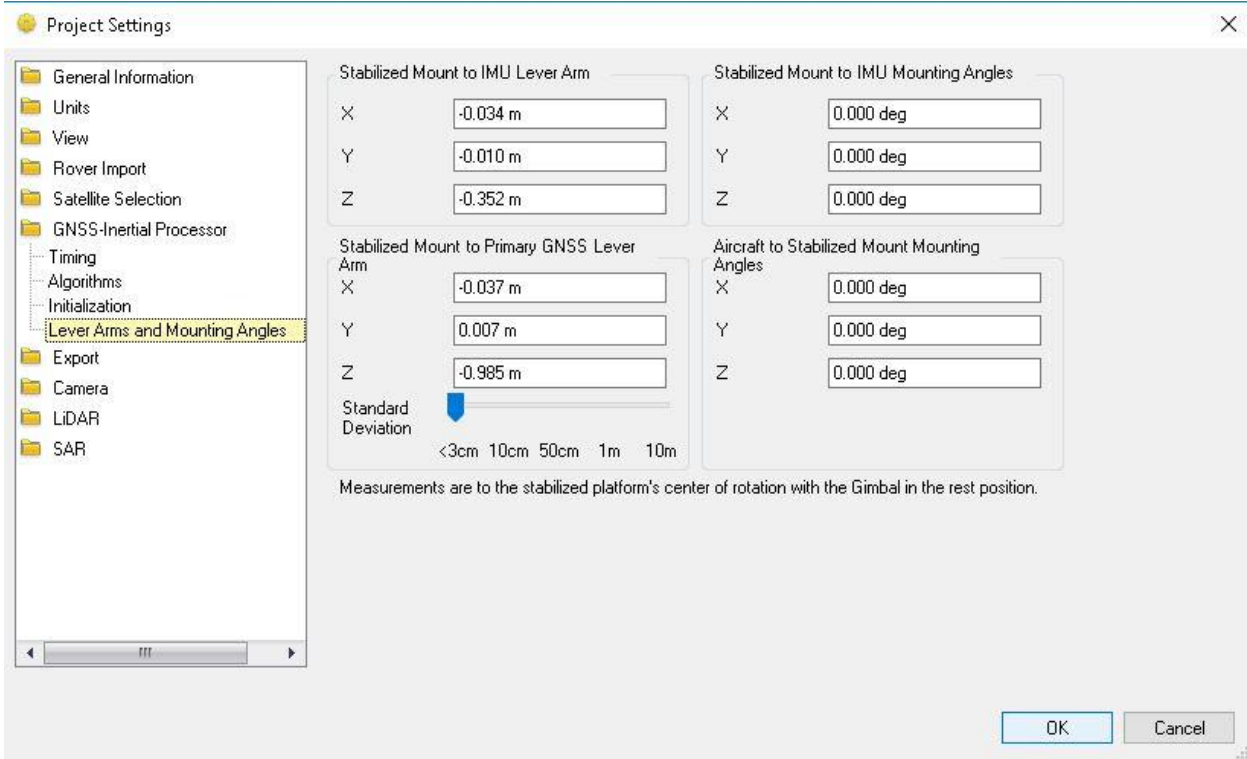


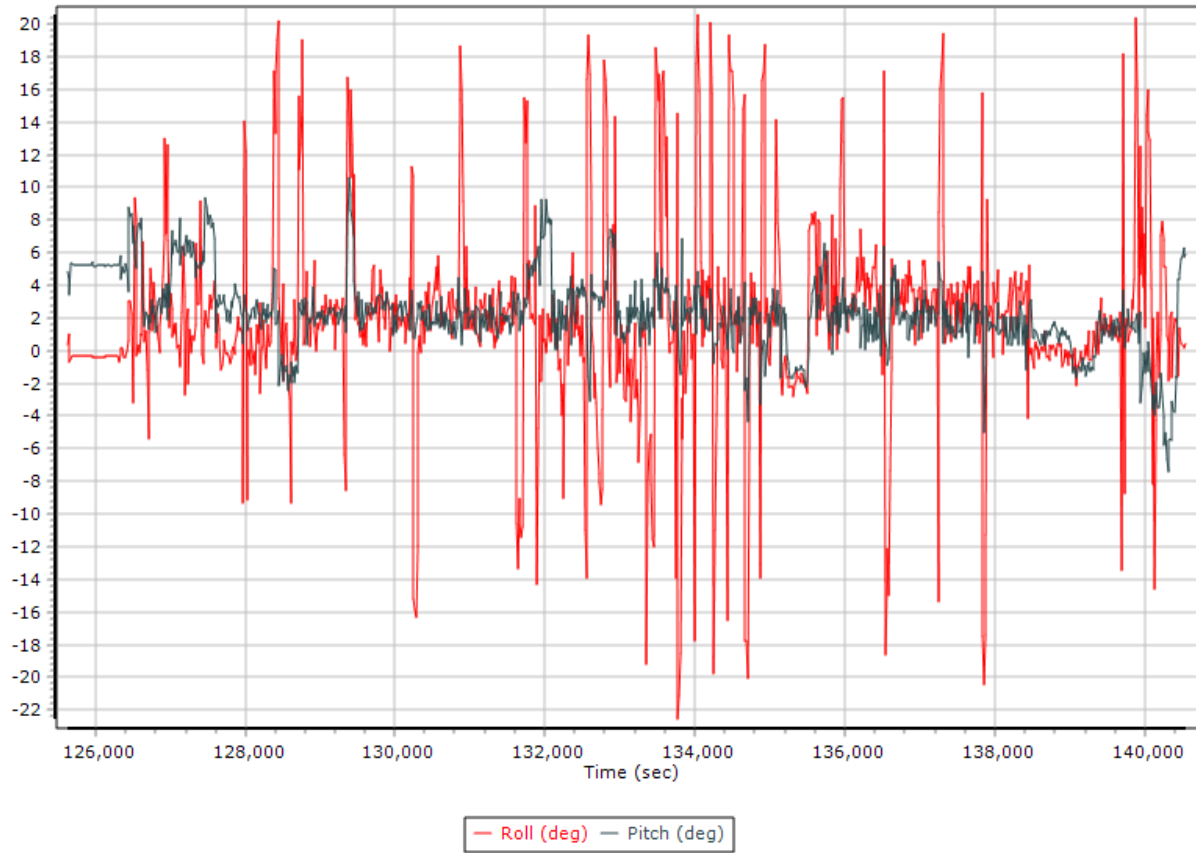
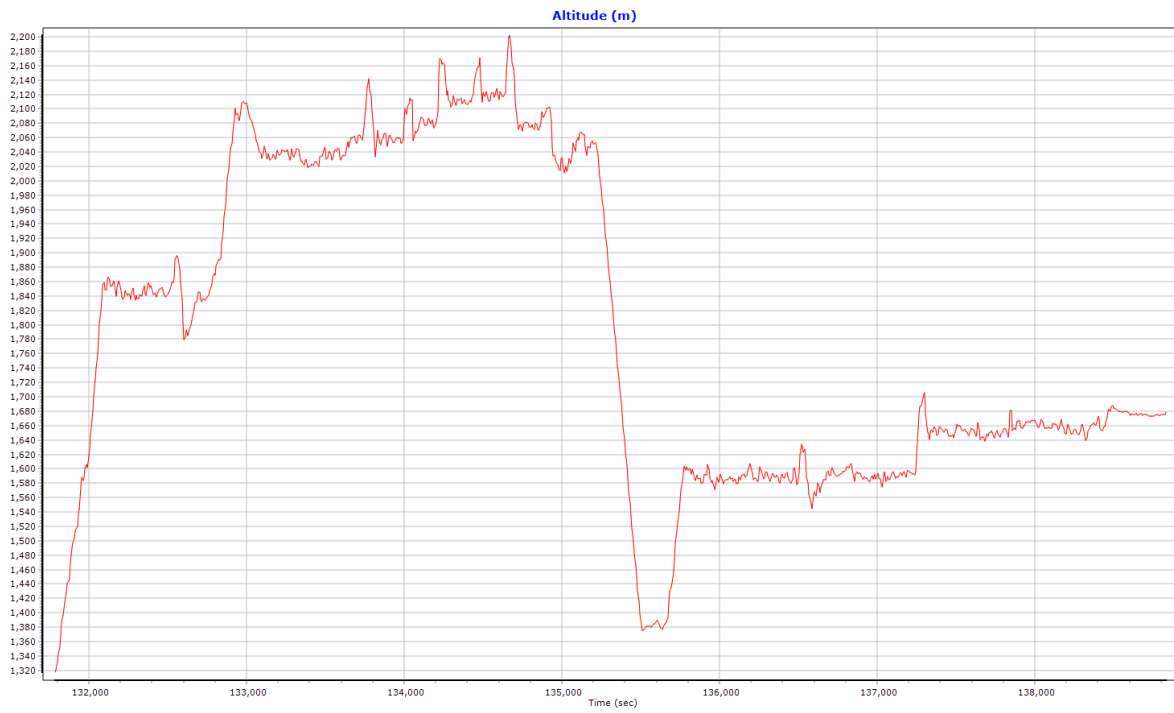


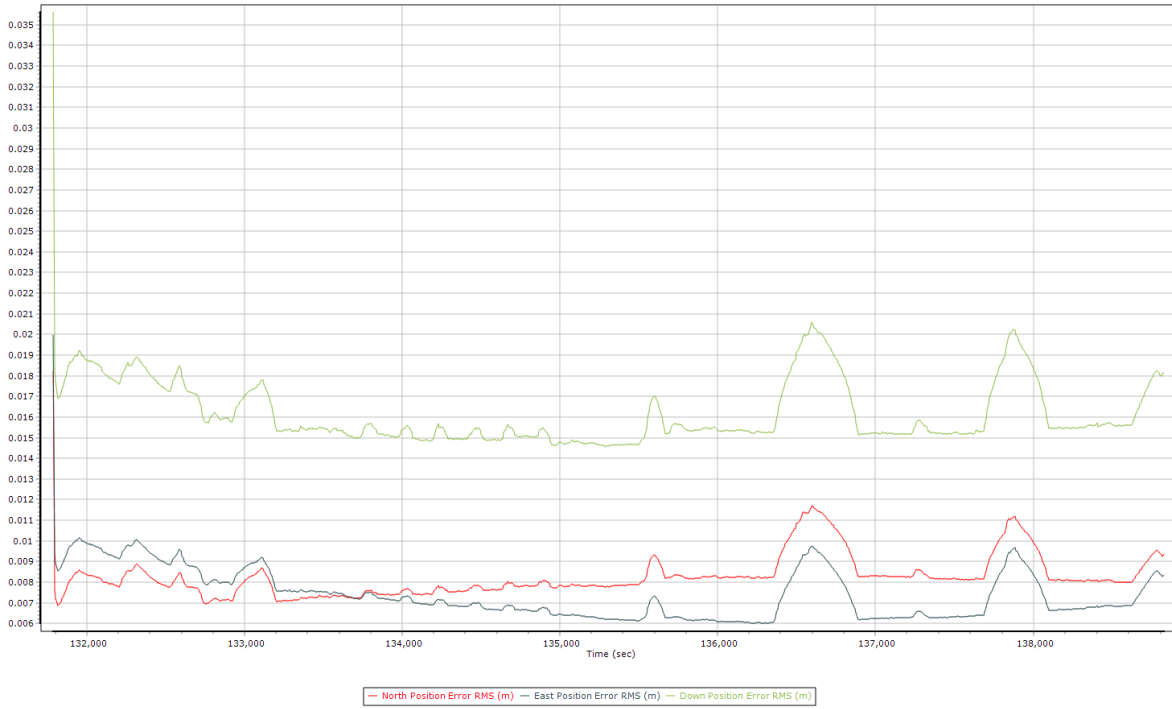


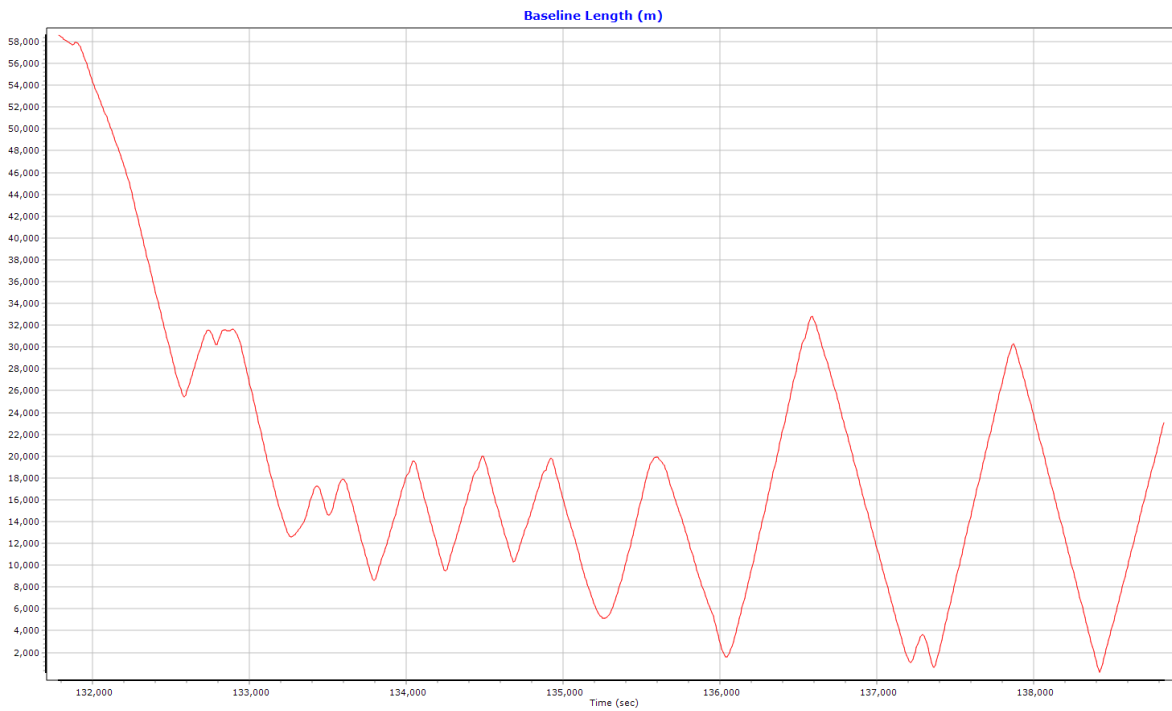
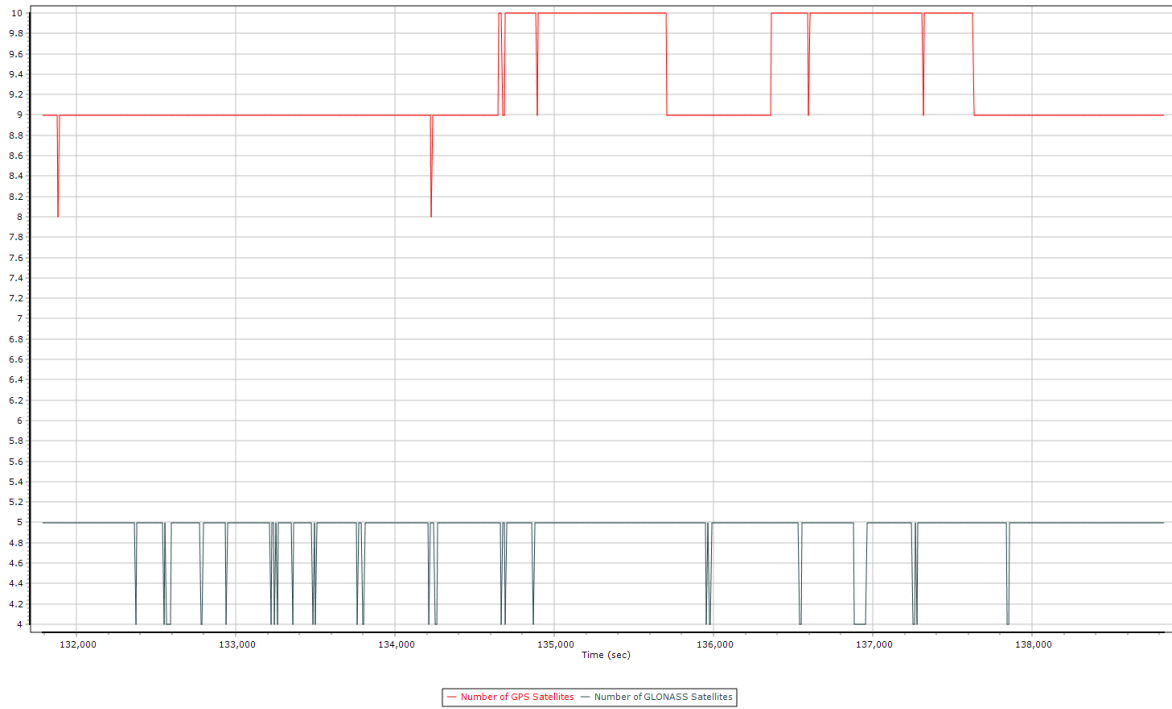
RBV18113A2

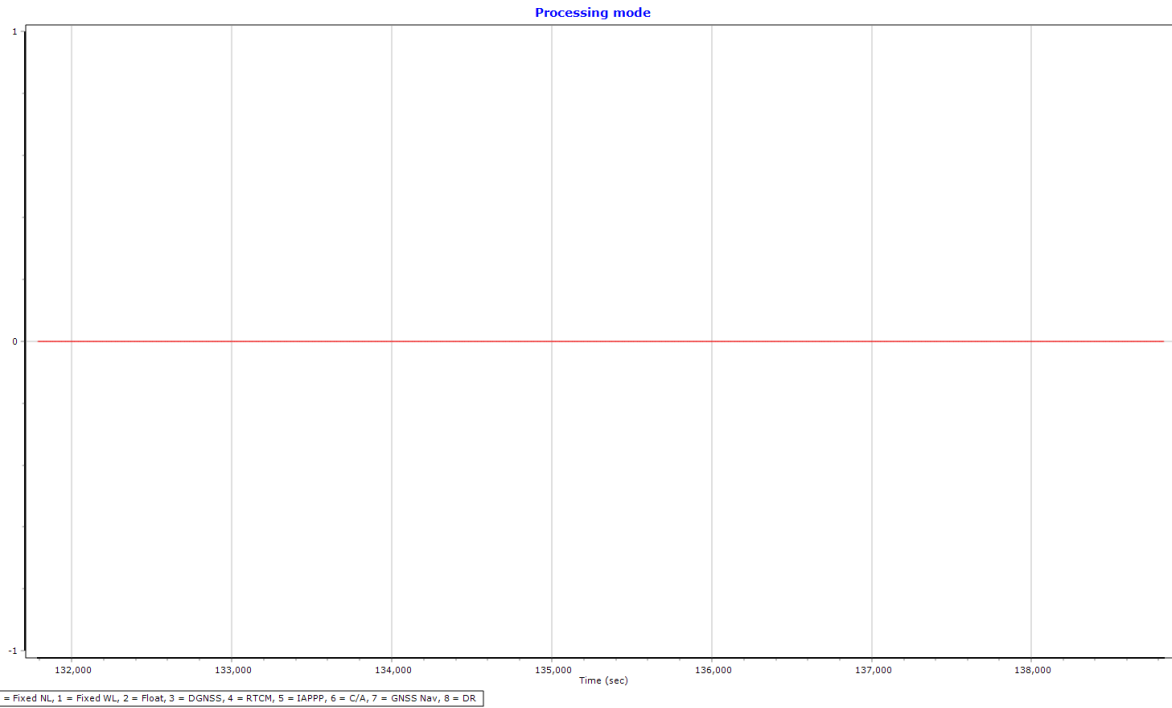
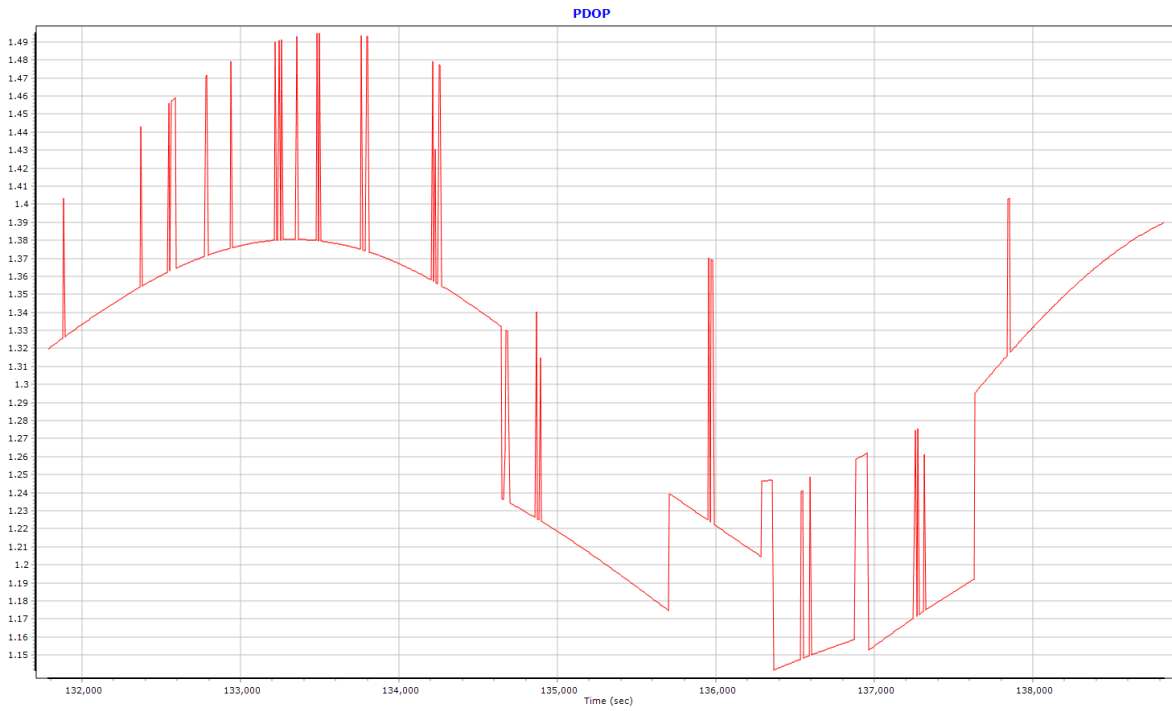




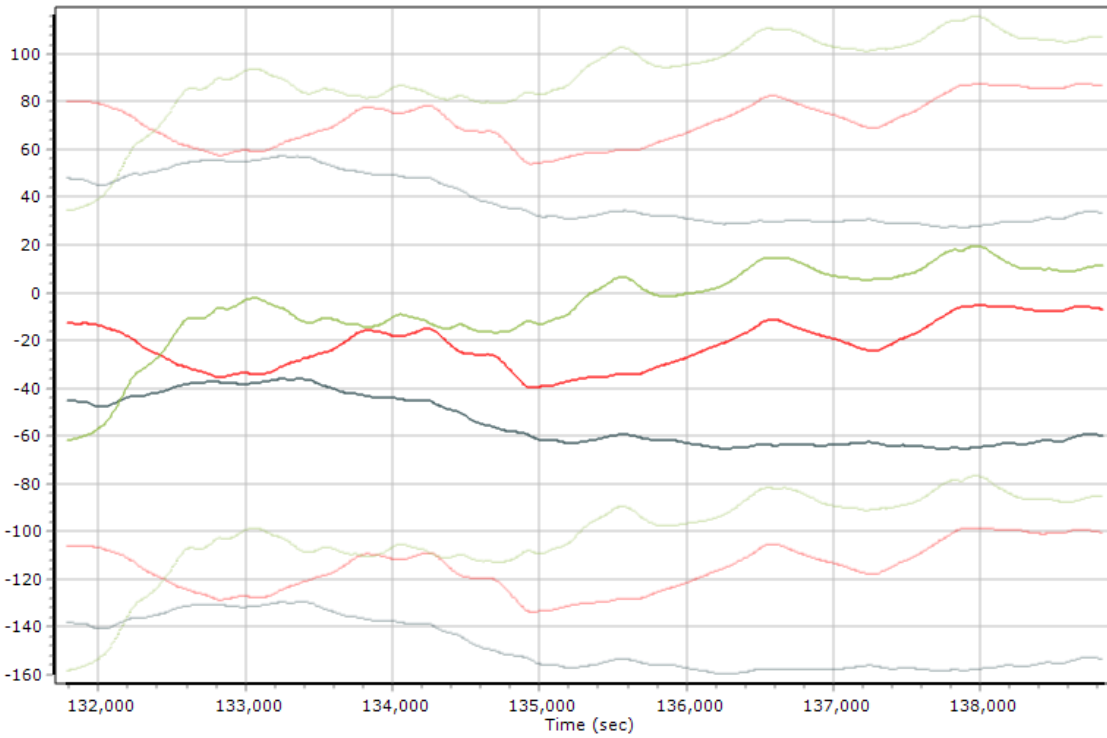




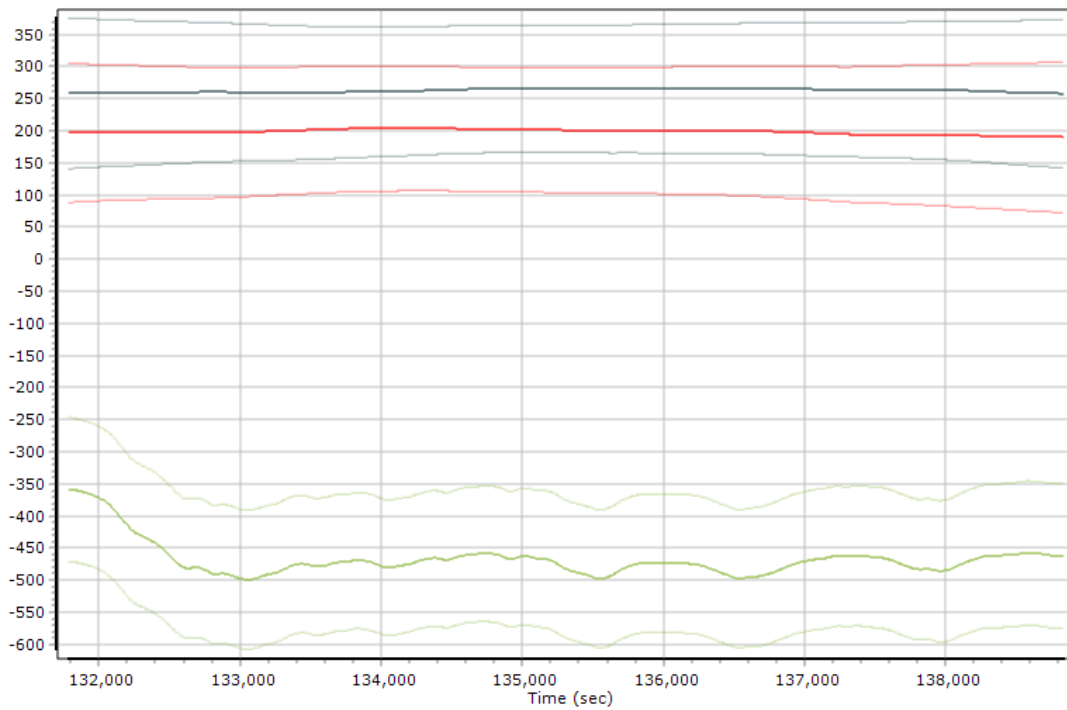




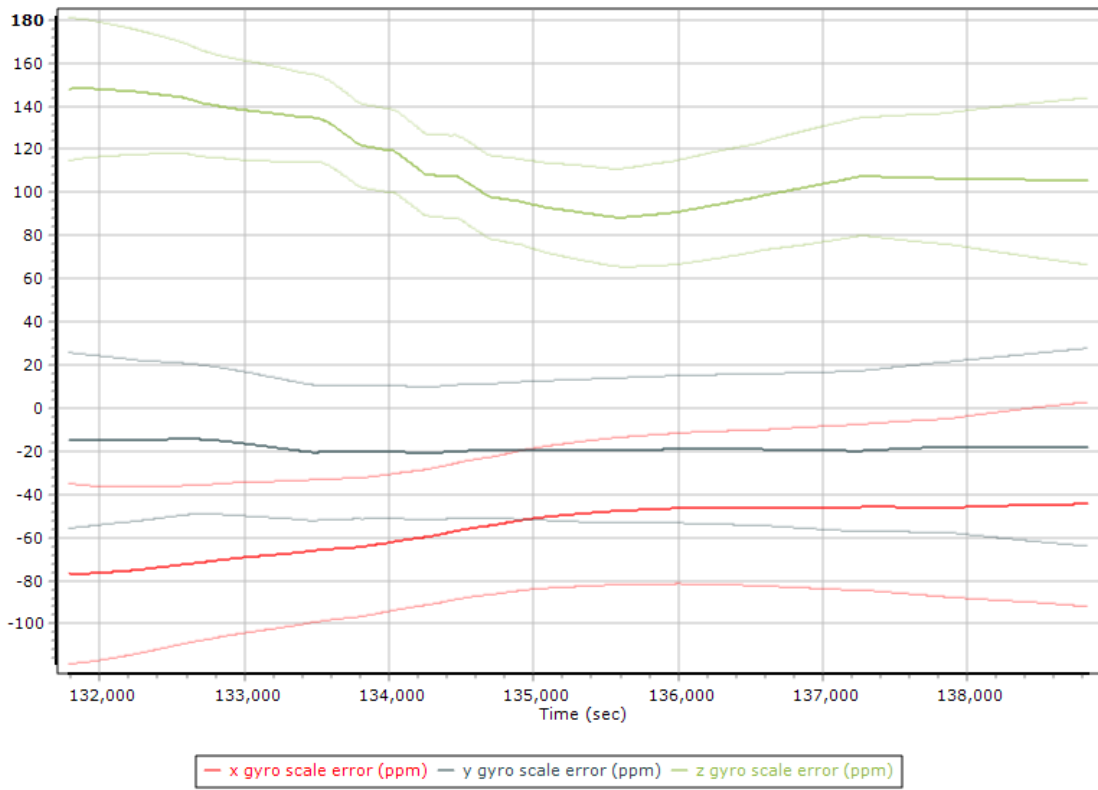
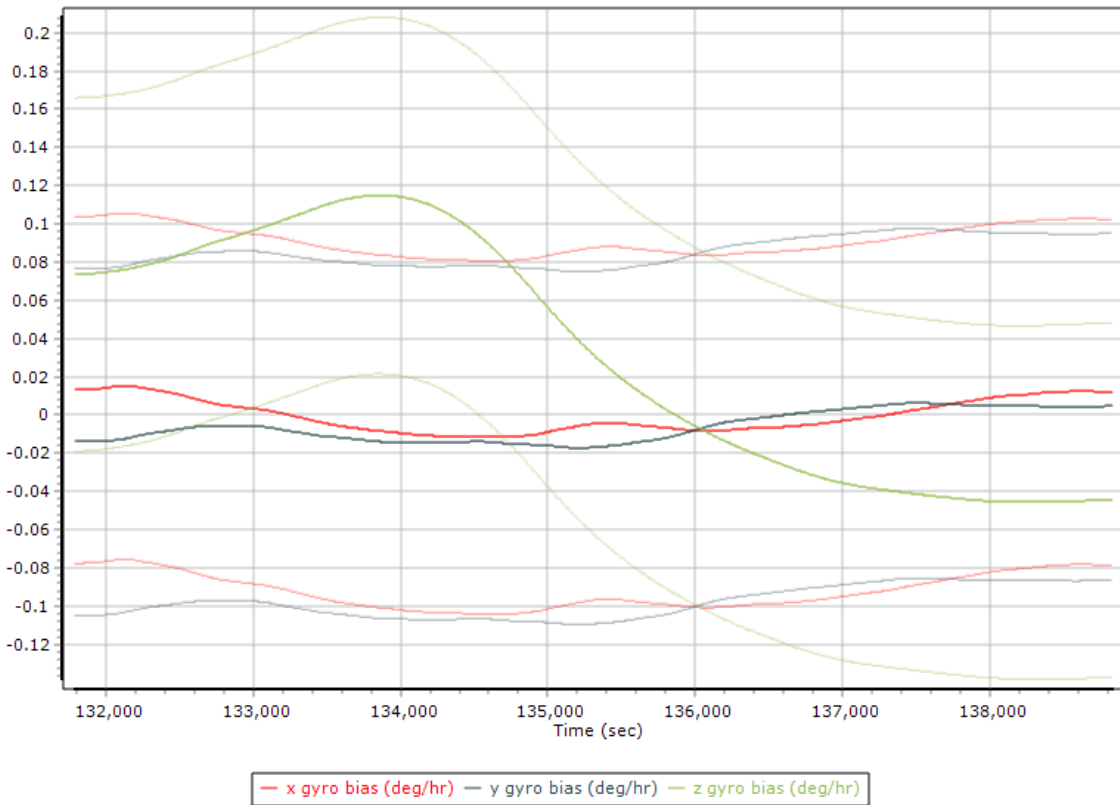
Sensor Errors



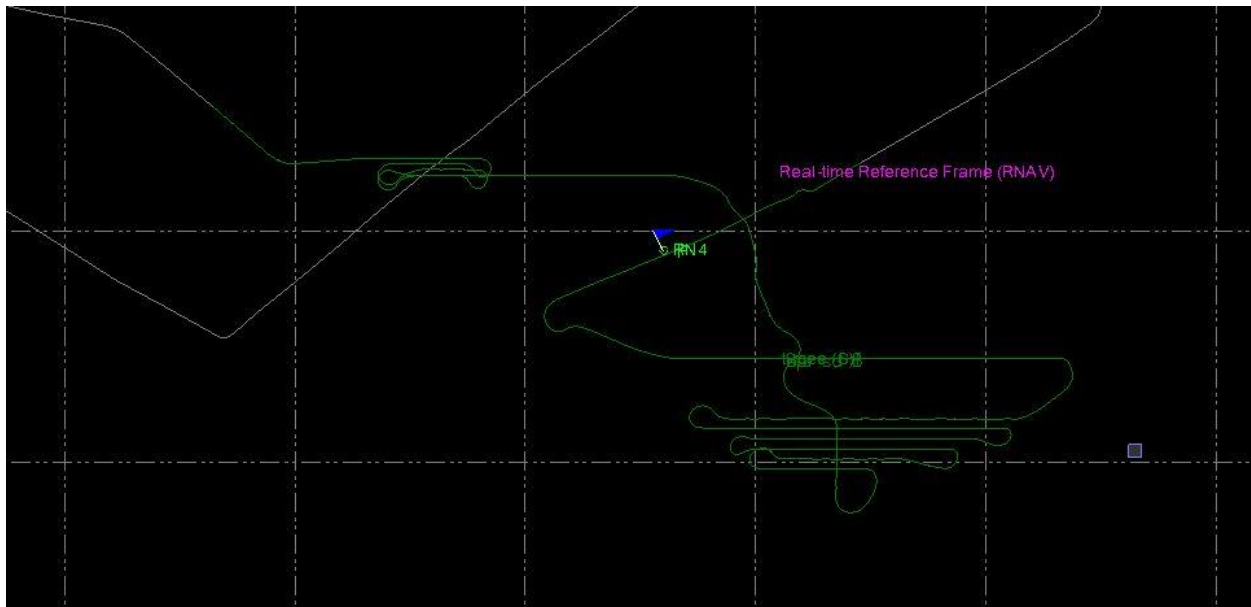
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



RBV18114A



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

Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.037 m	0.007 m	-0.985 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	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

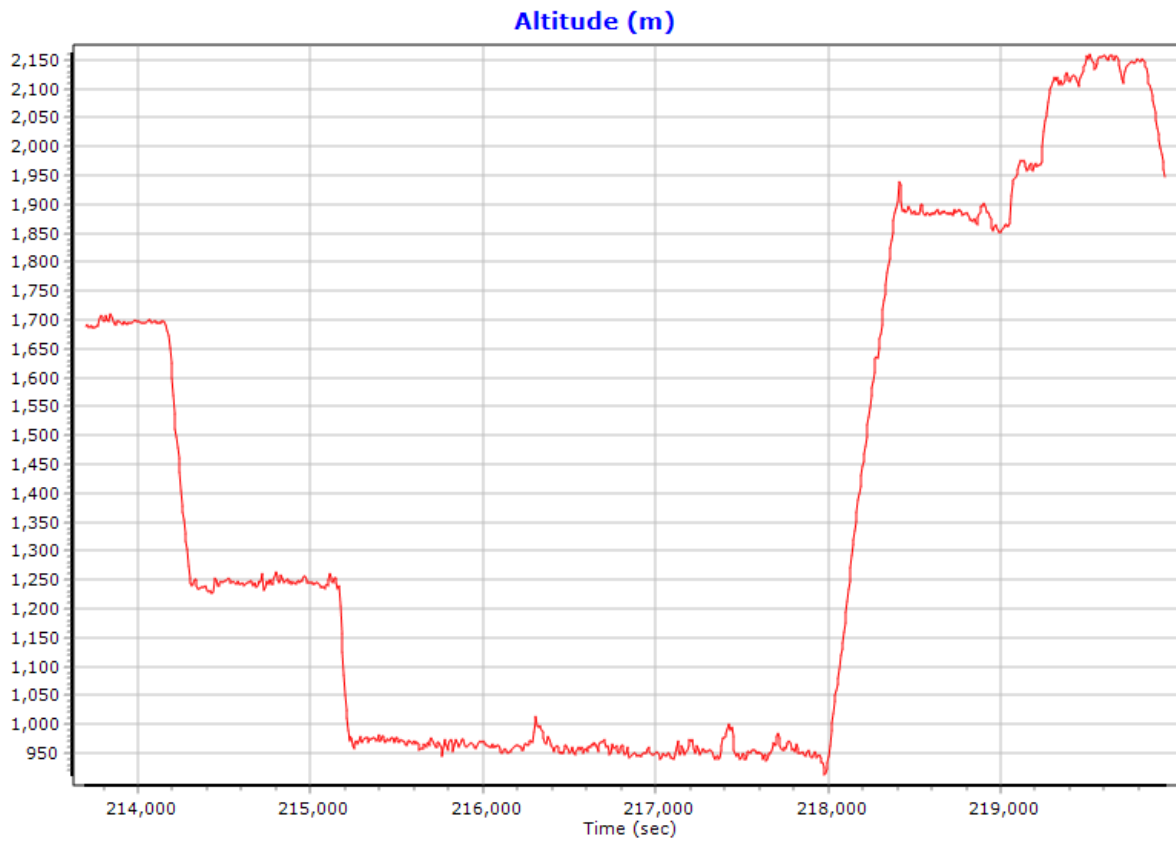
Project Settings

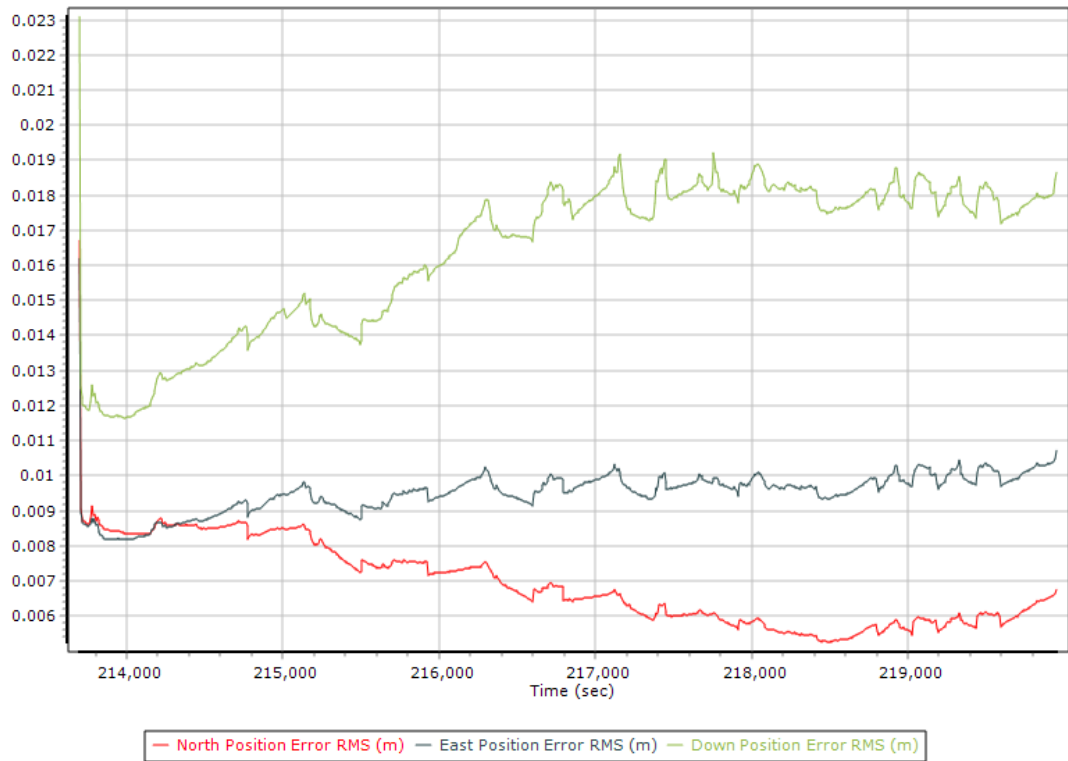
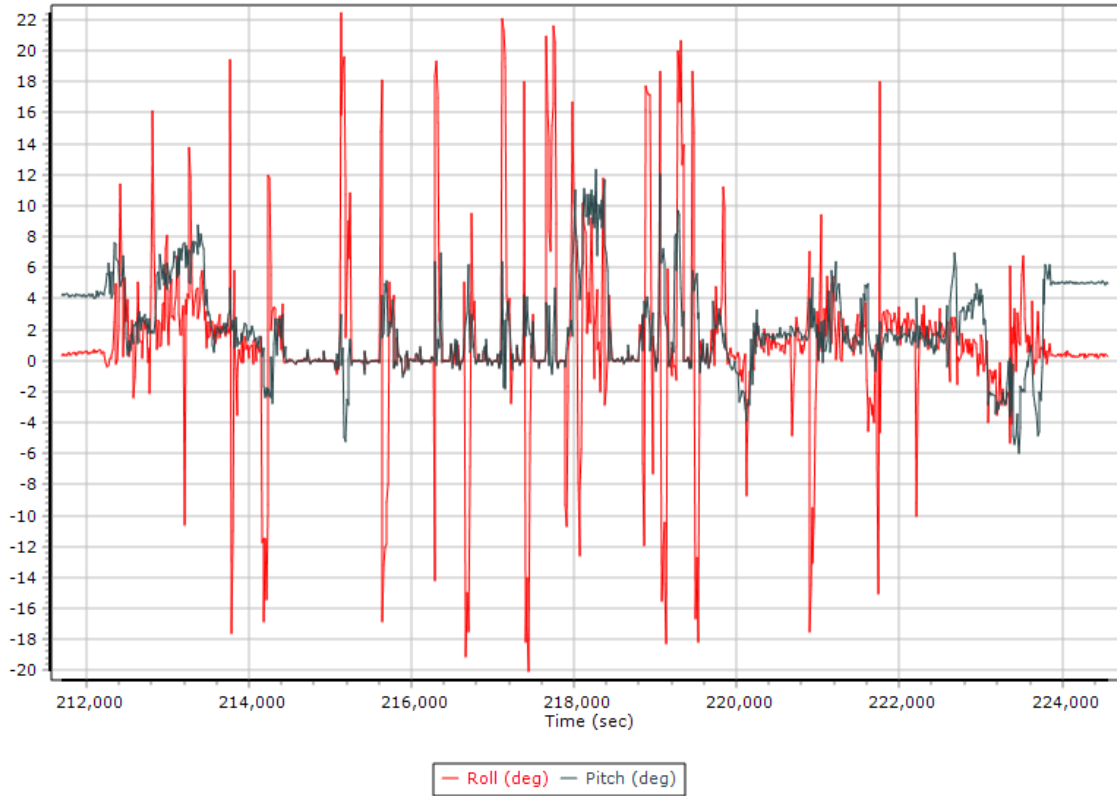
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
Timing
Algorithms
Initialization
Lever Arms and Mounting Angles
Export
Camera
LiDAR
SAR

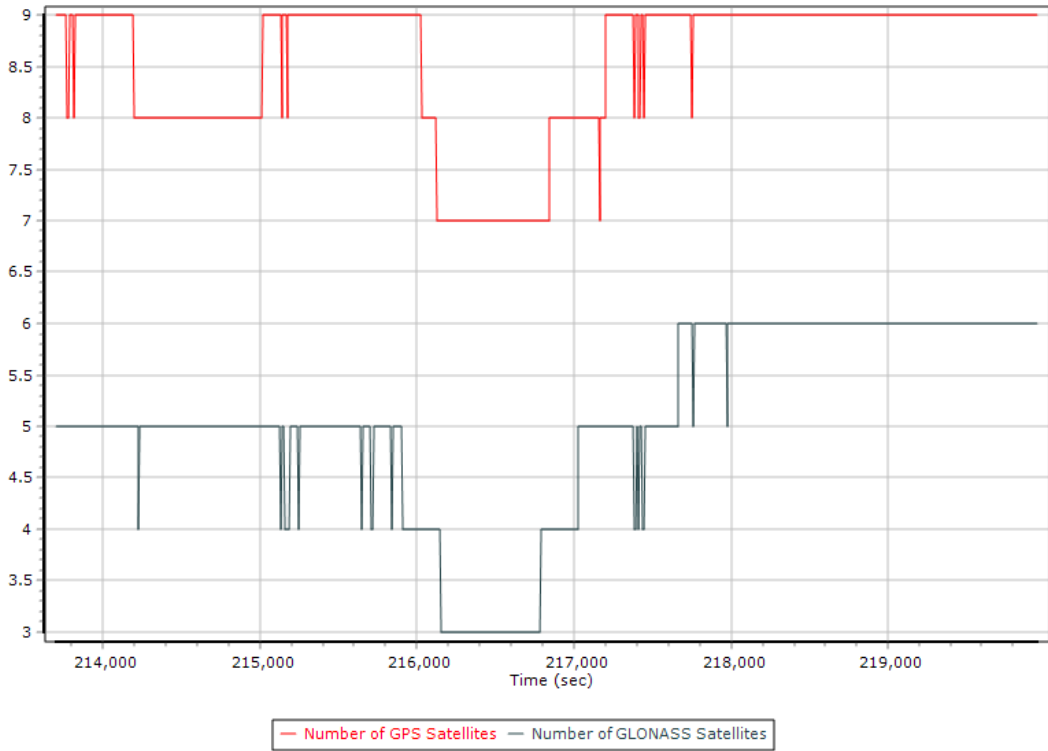
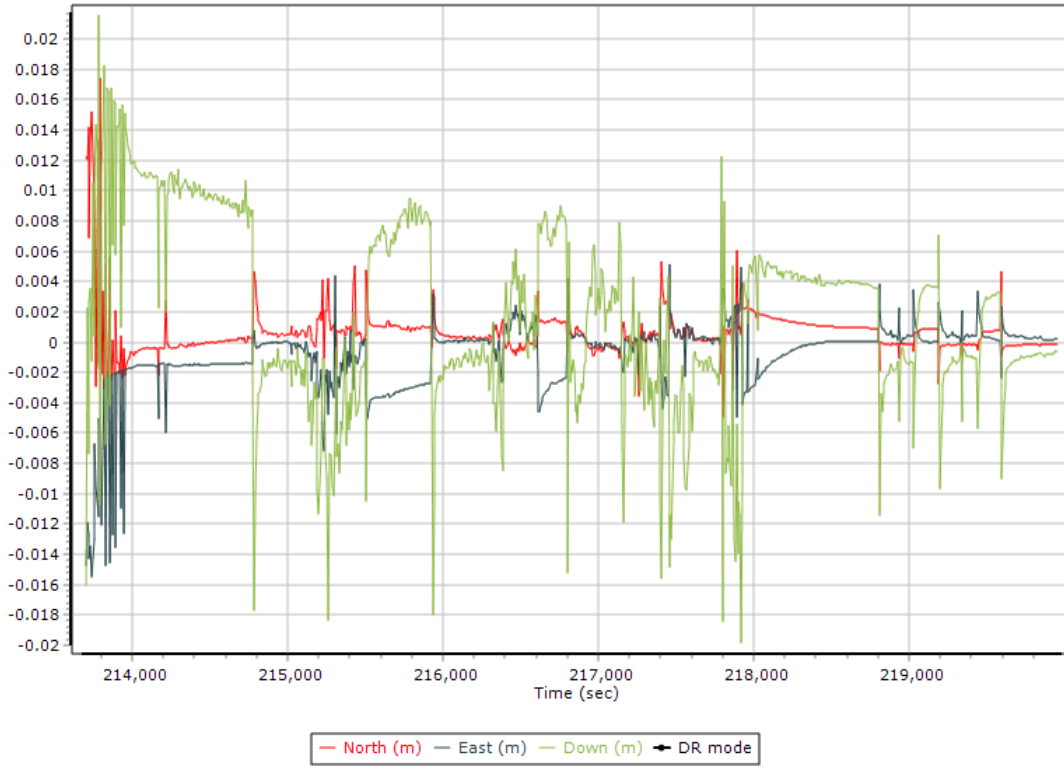
Timing
Start: 213700.000
End: 219957.081
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

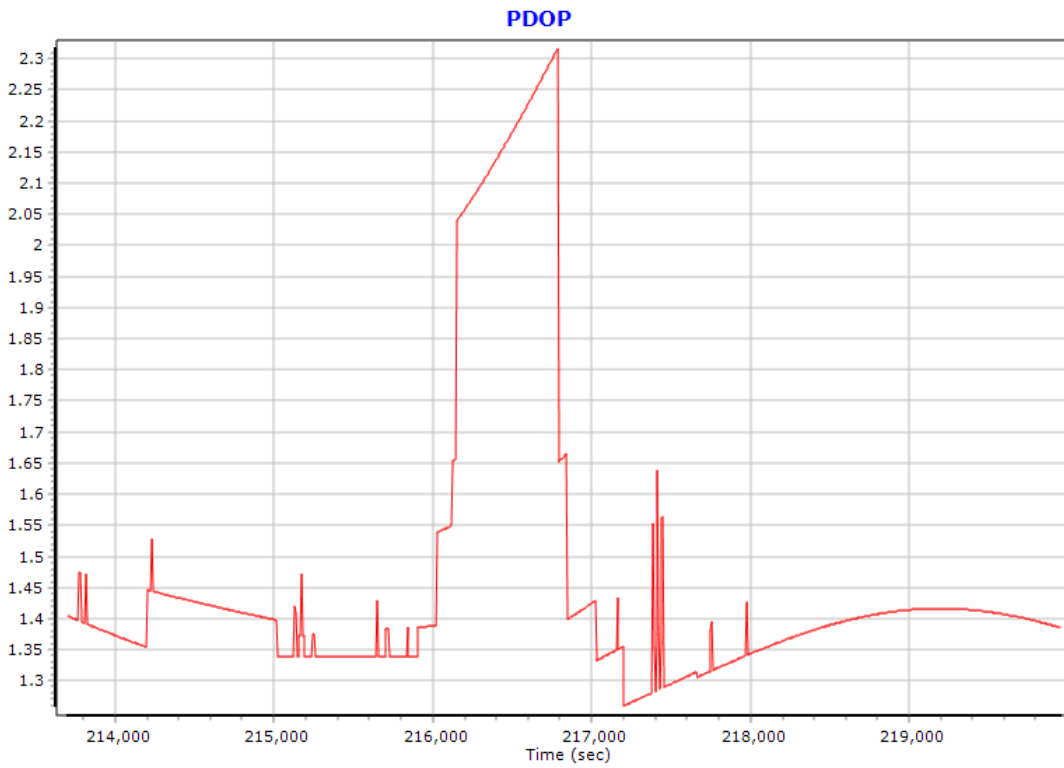
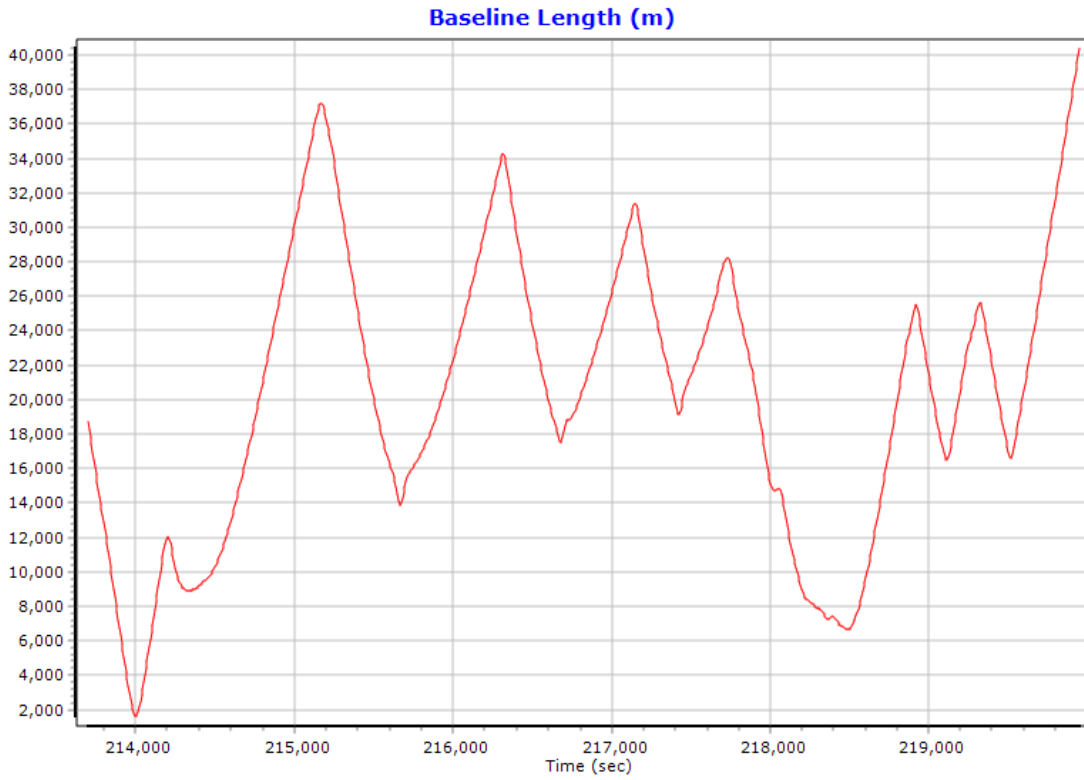
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel

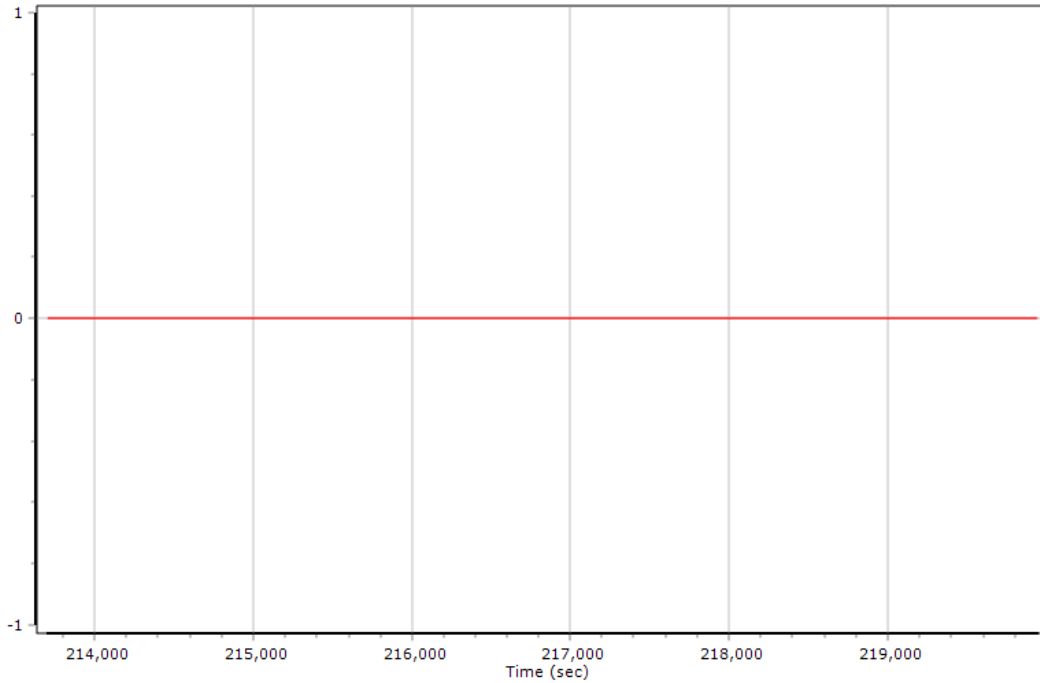






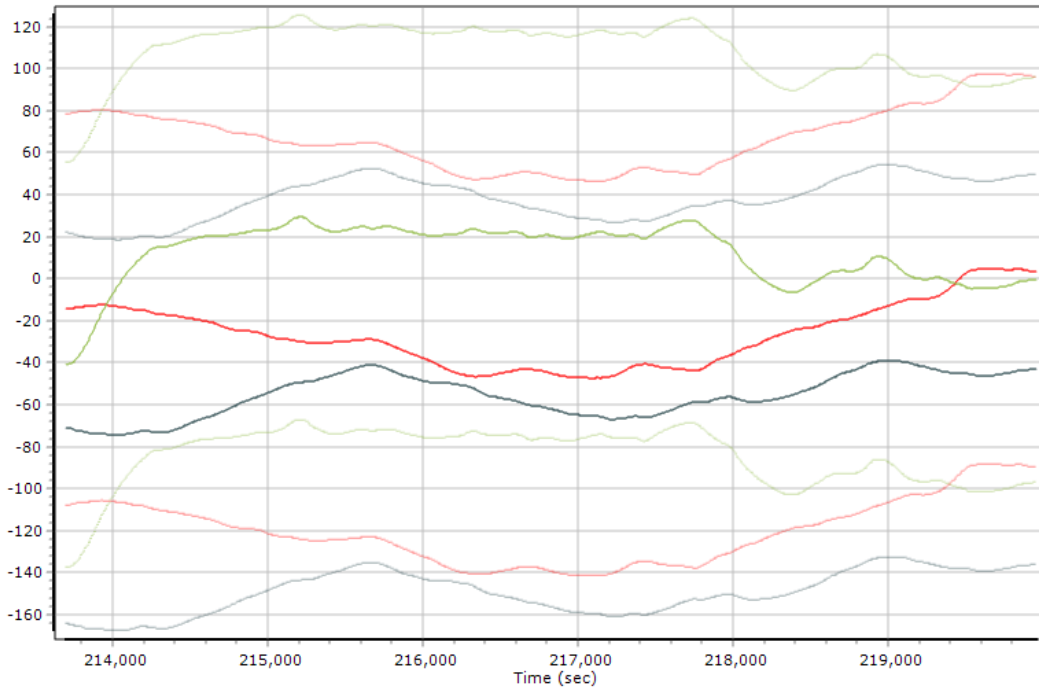


Processing mode

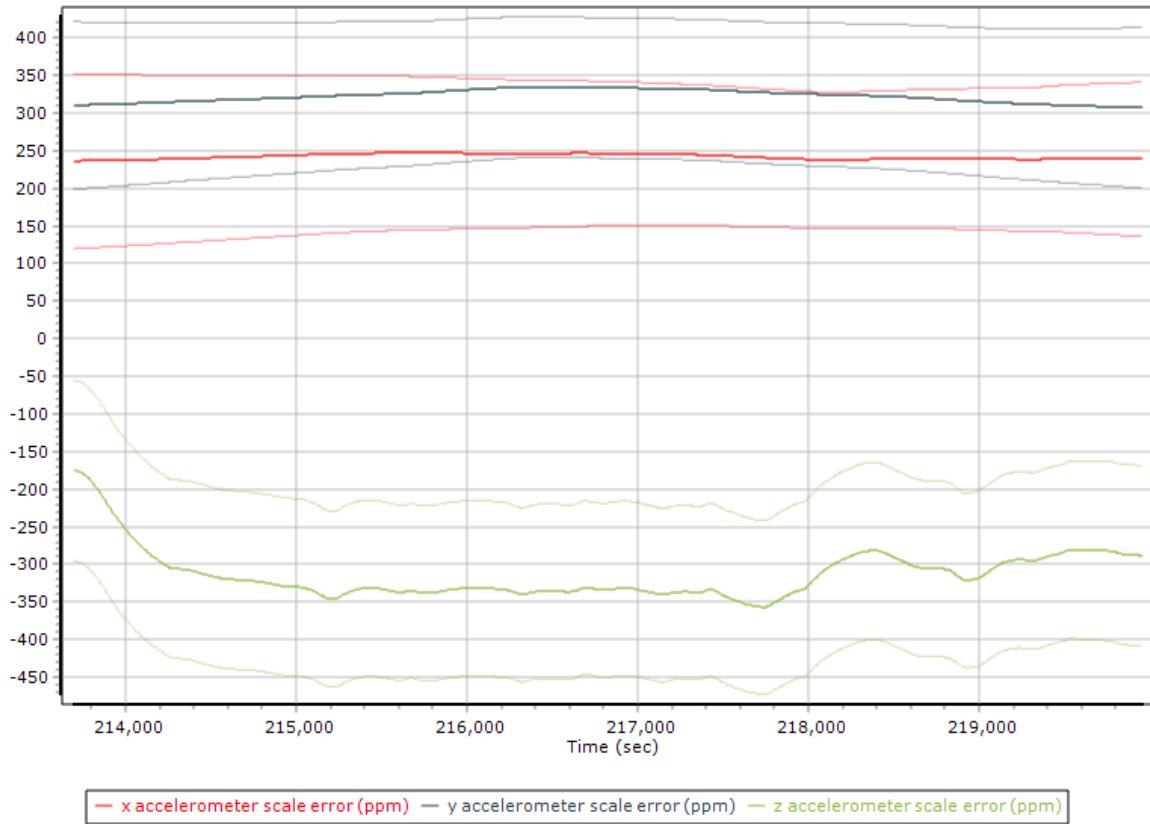


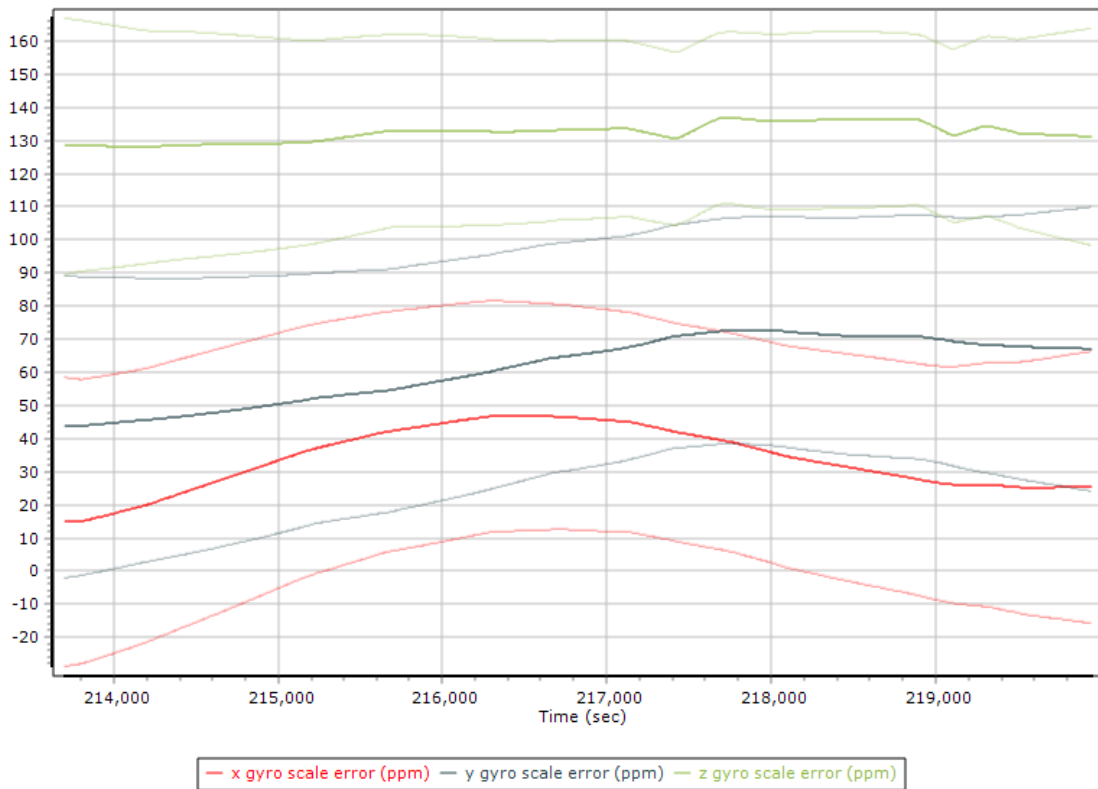
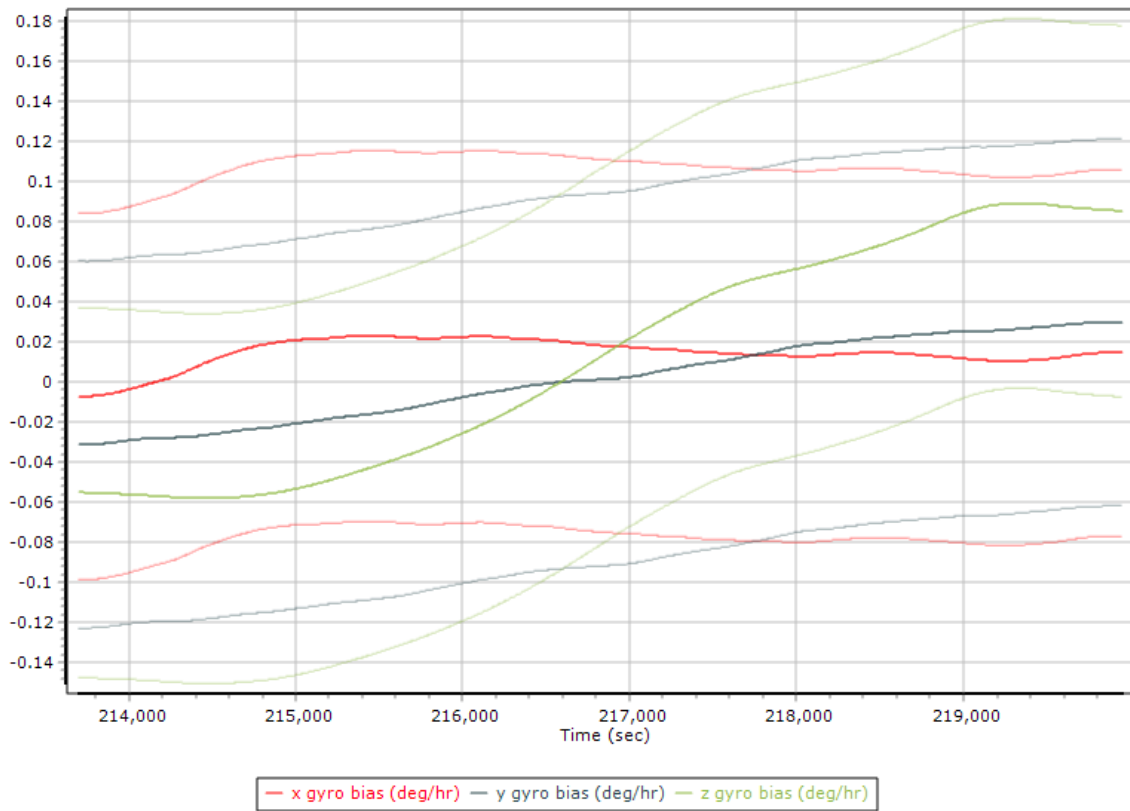
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

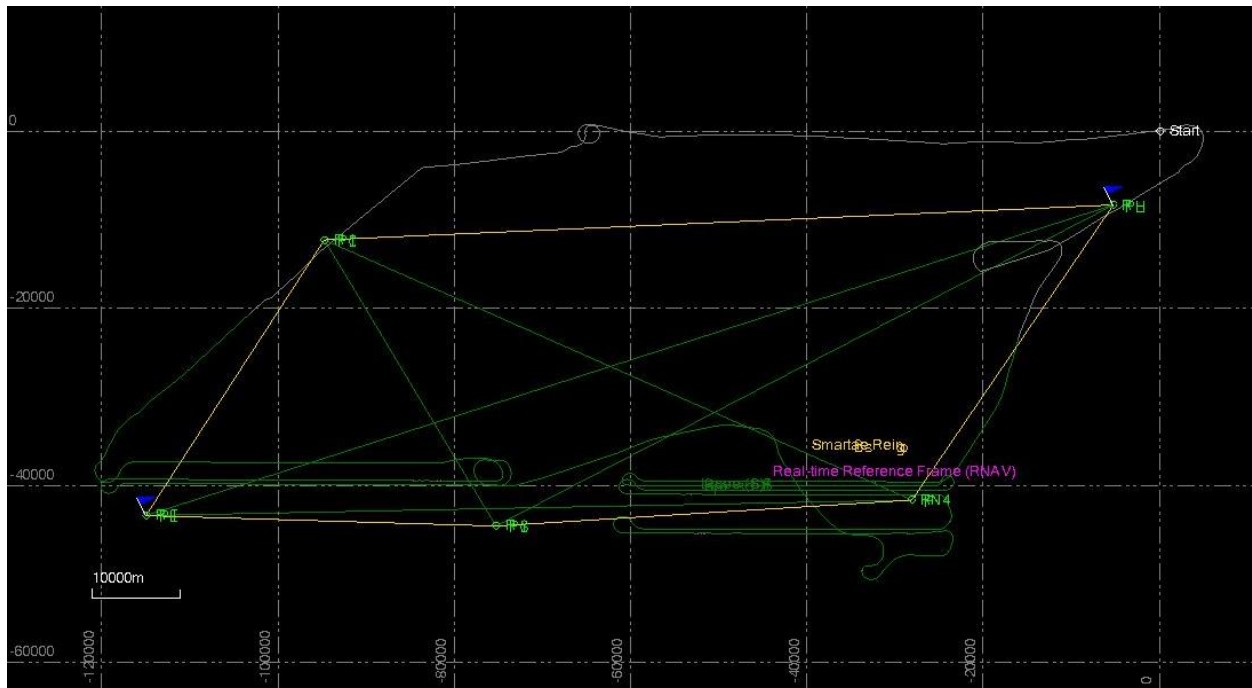


— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)





RBV18115A



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

Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.037 m	0.007 m	-0.985 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	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

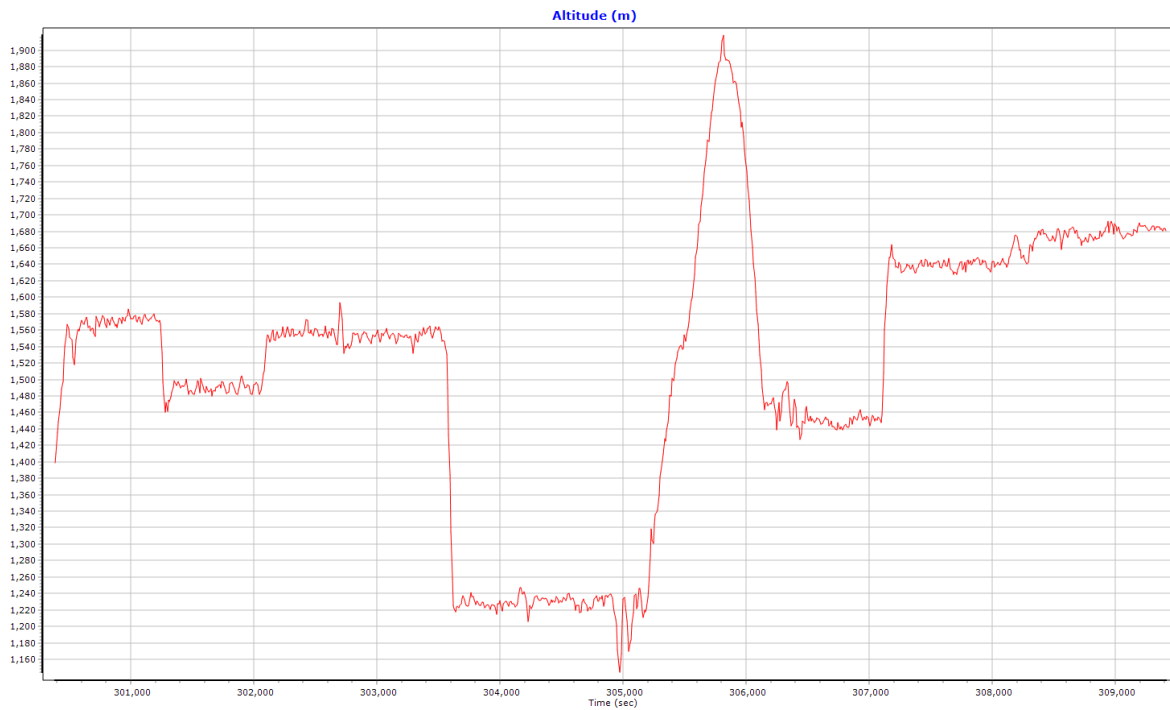
Start: 300386.544
End: 309425.664

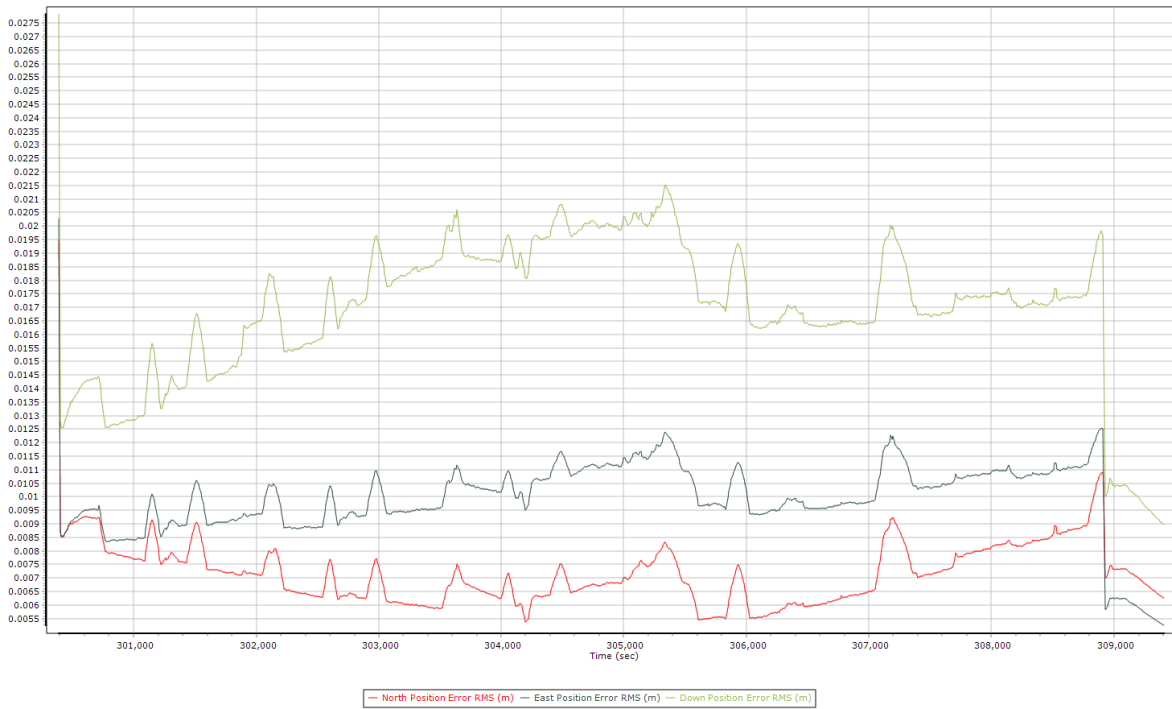
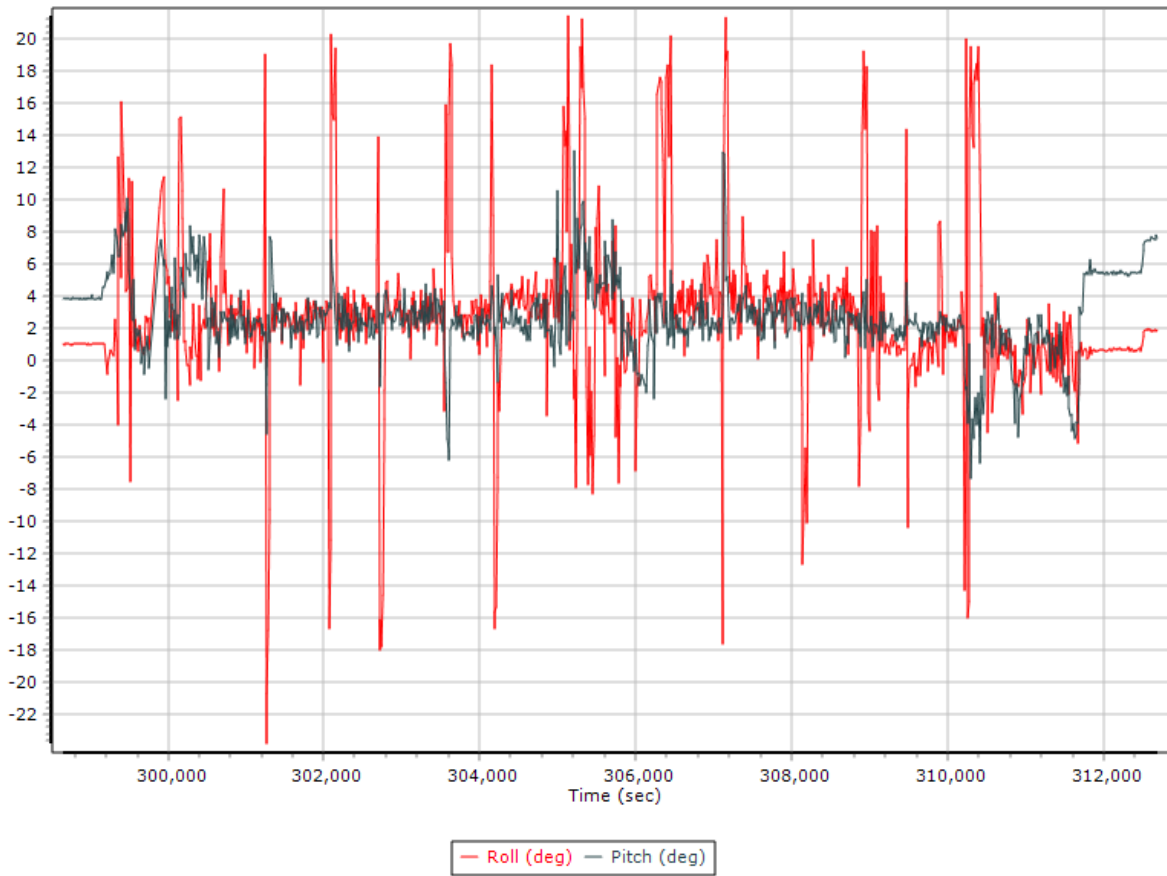
Entire time interval
 Seconds of start week

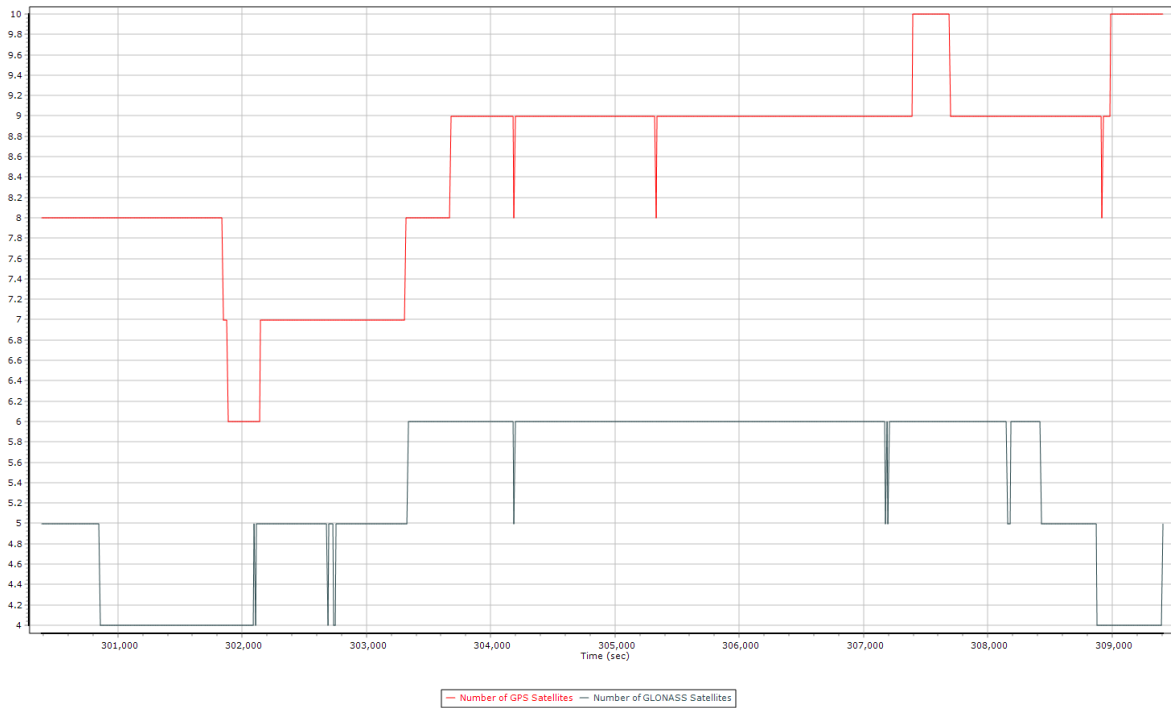
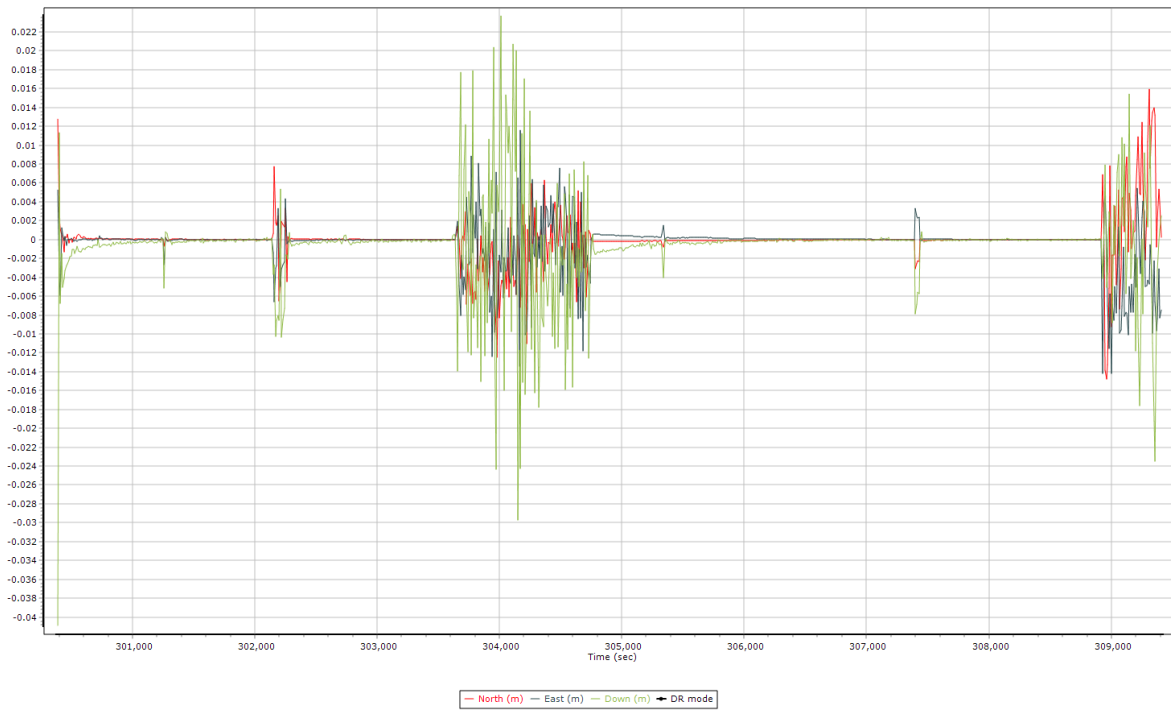
UTC Offset: 18.000

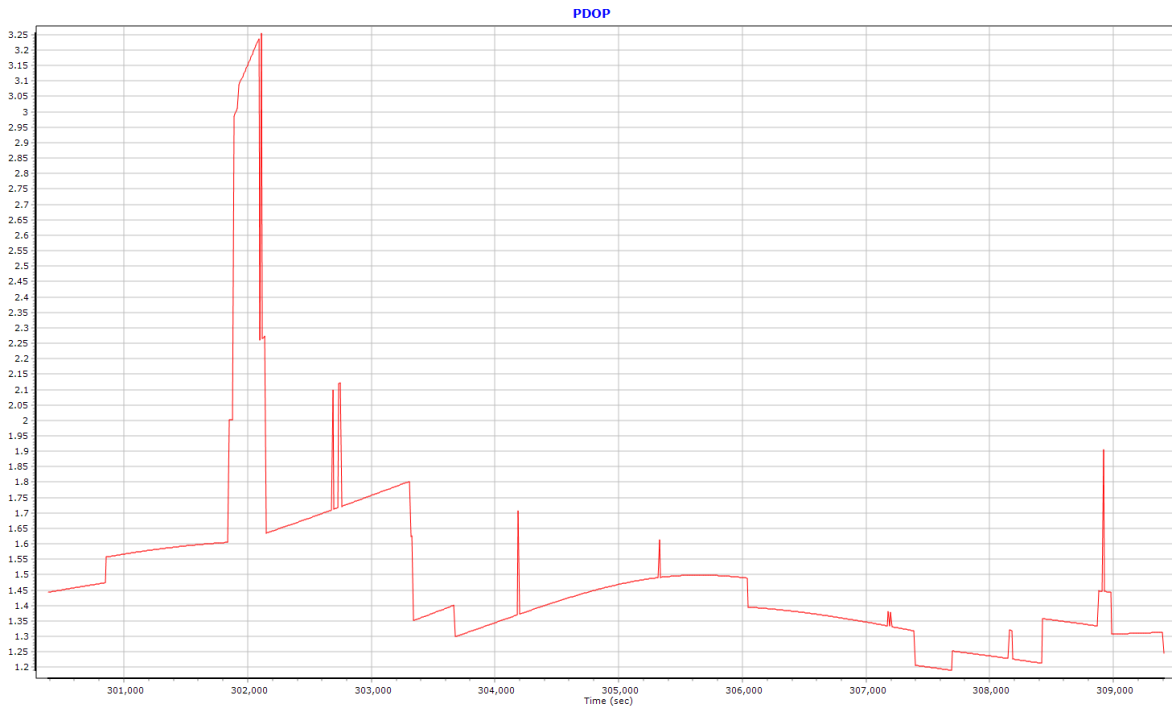
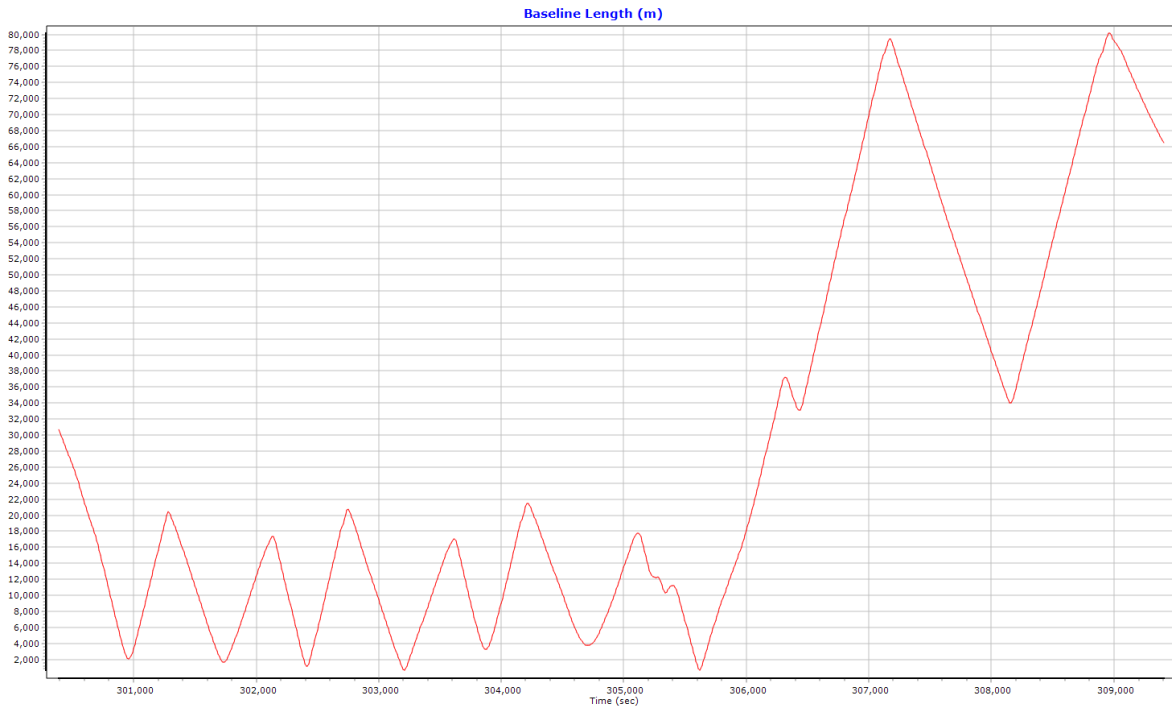
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

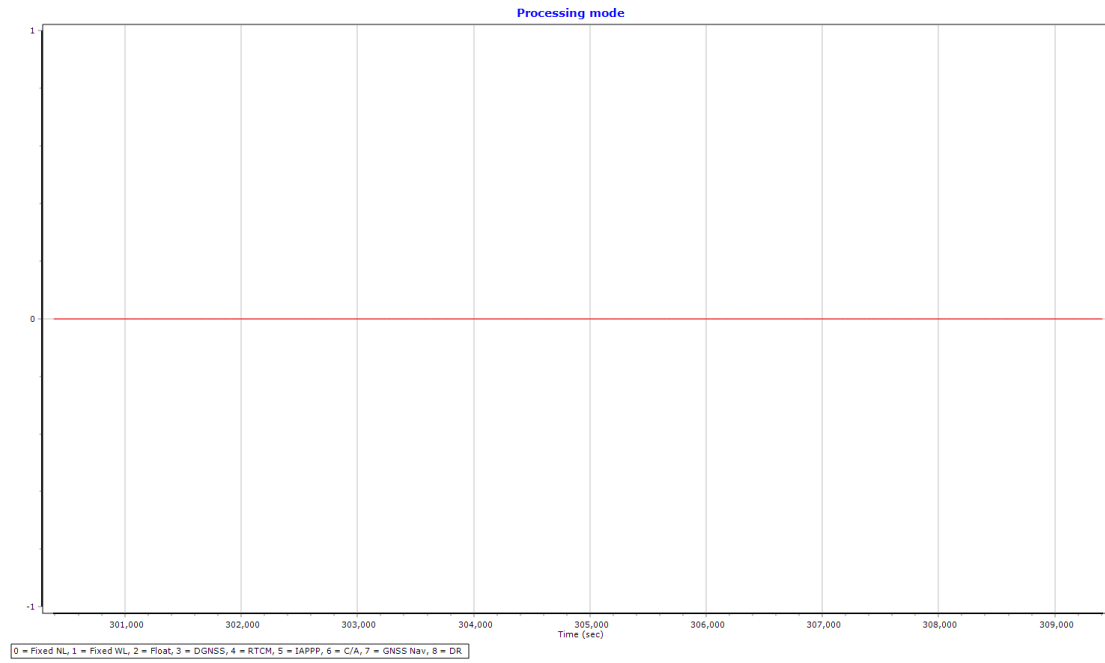
OK Cancel



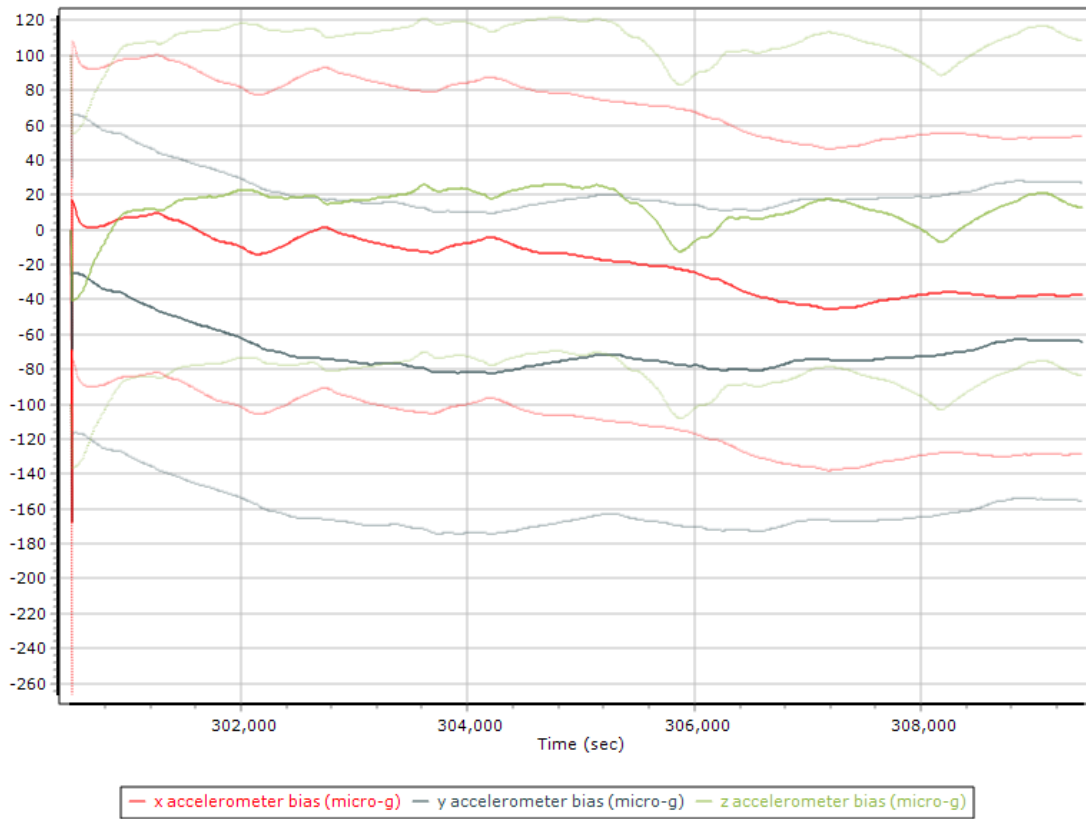


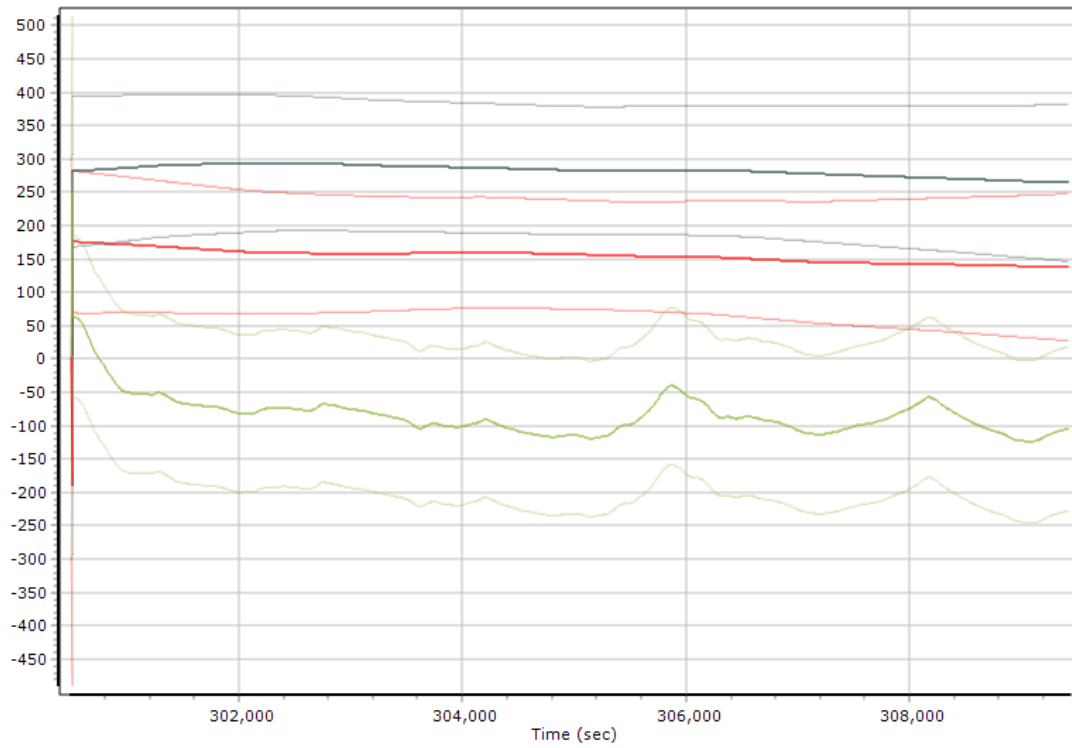




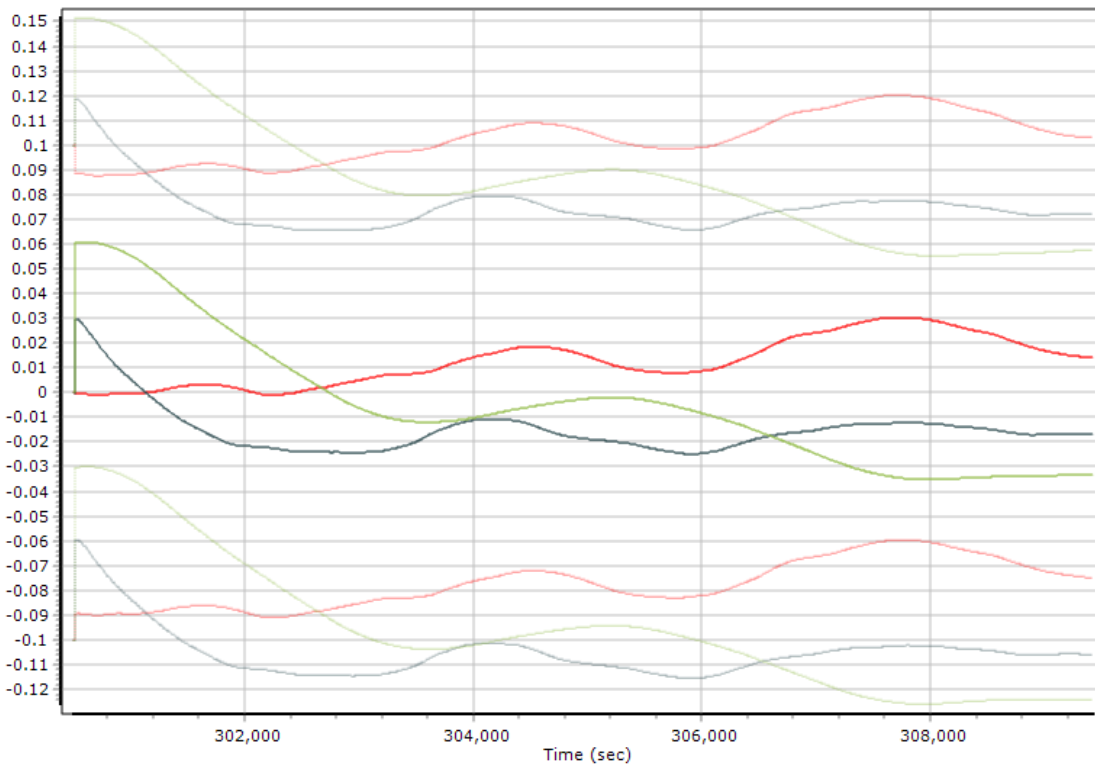


Sensor Errors

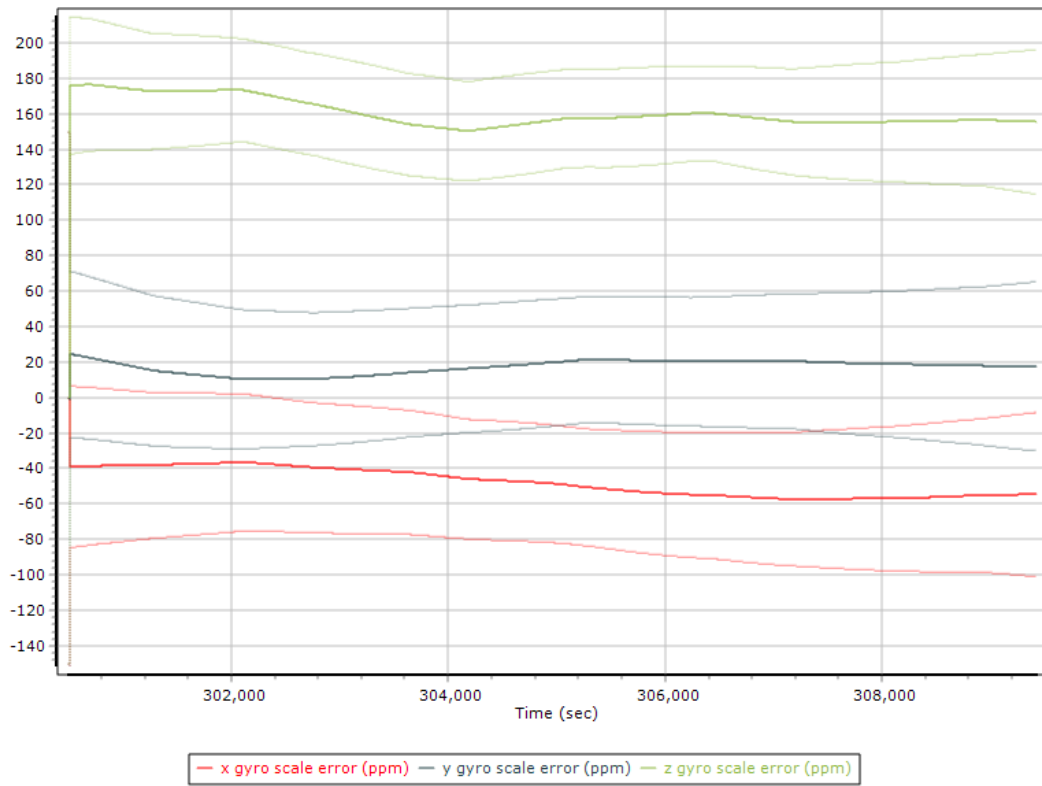




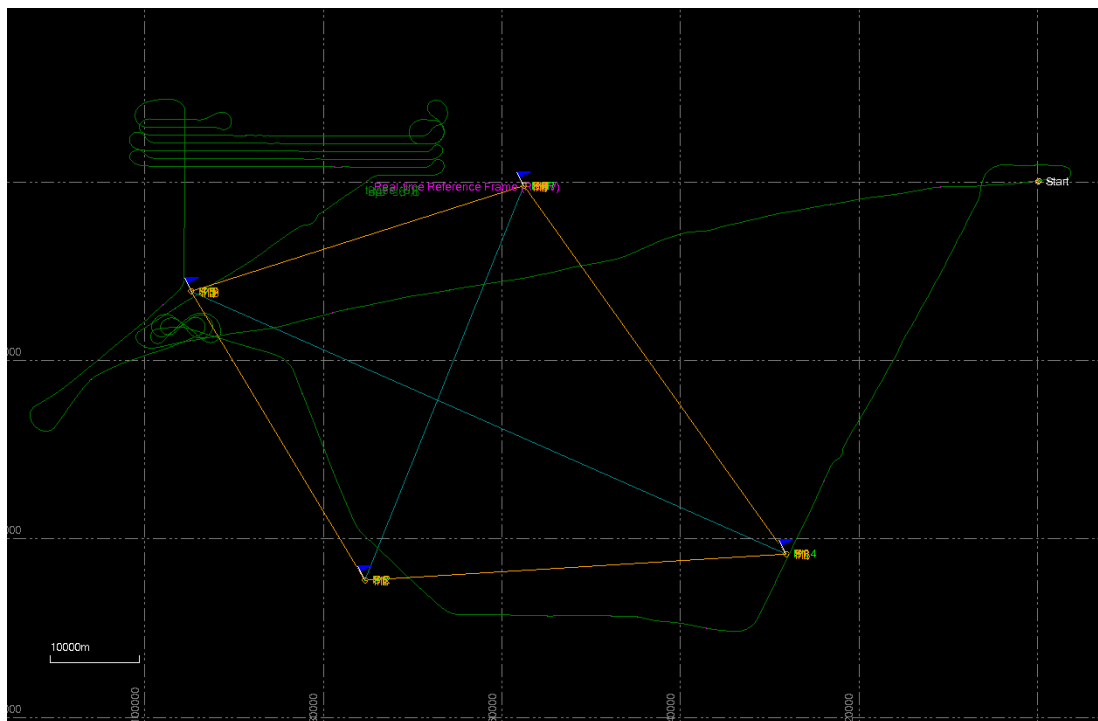
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



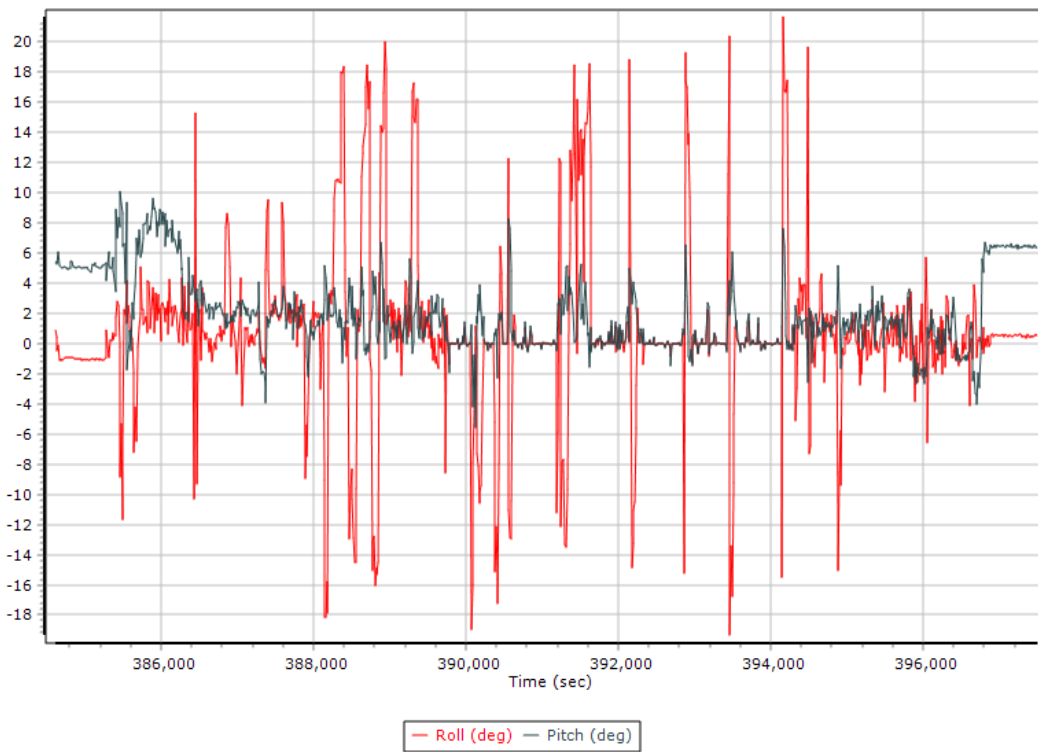
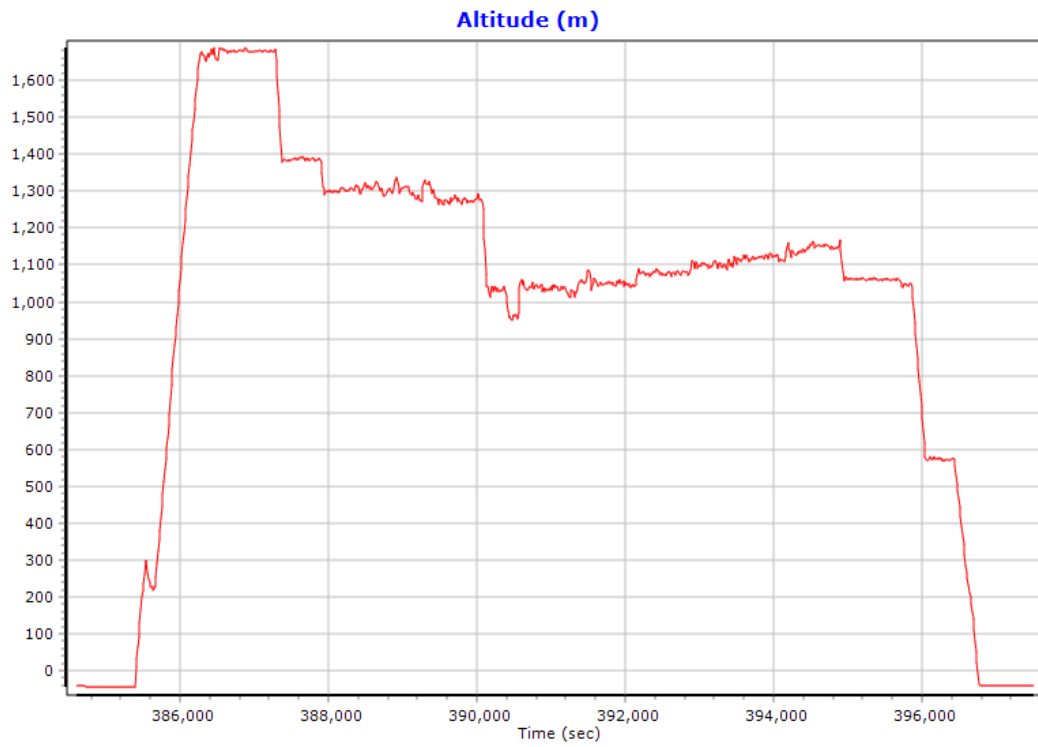
RBV18116A

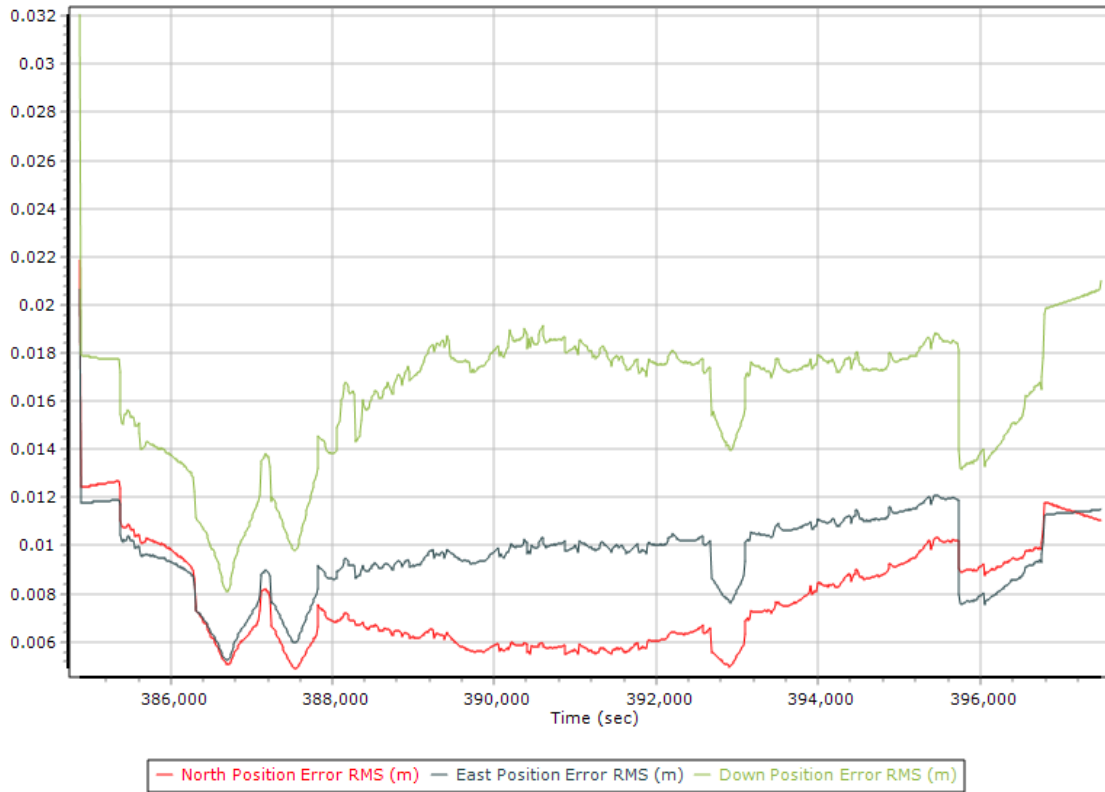


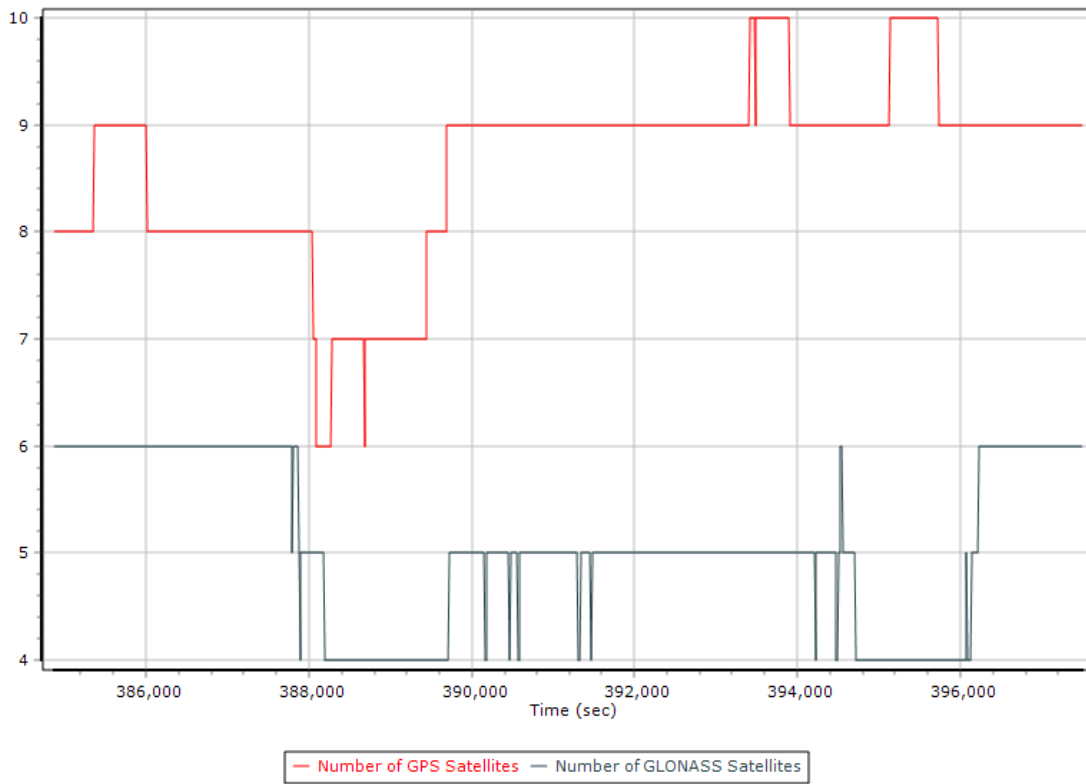
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 deg"/>
Stabilized Mount to Primary GNSS Lever Arm		Aircraft to Stabilized Mount Mounting Angles	
Arm		Angles	
X	<input type="text" value="-0.037 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="0.007 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.985 m"/>	Z	<input type="text" value="0.000 deg"/>
Standard Deviation	<input type="range" value="3cm"/>		
	<3cm 10cm 50cm 1m 10m		

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

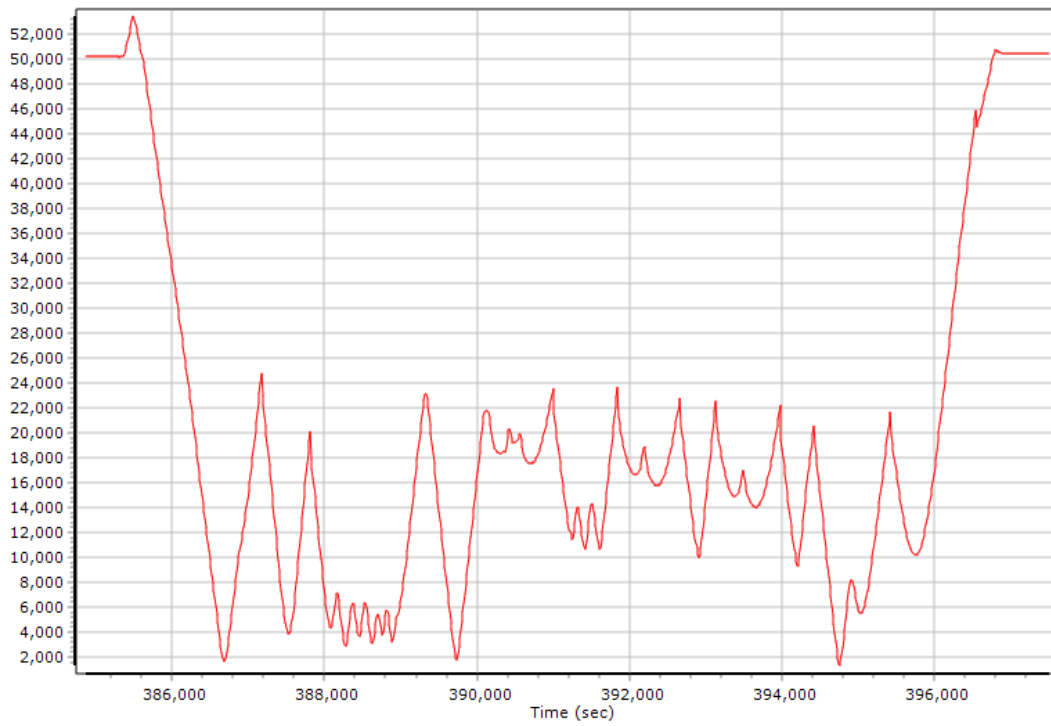
Timing									
Start	<input type="text" value="384603.000"/>								
End	<input type="text" value="397508.000"/>								
<input checked="" type="checkbox"/> Entire time interval									
<input checked="" type="checkbox"/> Seconds of start week									
UTC Offset	<input type="text" value="18.000"/>								
<table border="1"><thead><tr><th>Data</th><th>Incr. (sec)</th></tr></thead><tbody><tr><td>Output Record</td><td>0.005000</td></tr><tr><td>IMU</td><td>0.005000</td></tr><tr><td>Primary GNSS</td><td>1.000000</td></tr></tbody></table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000	
Data	Incr. (sec)								
Output Record	0.005000								
IMU	0.005000								
Primary GNSS	1.000000								



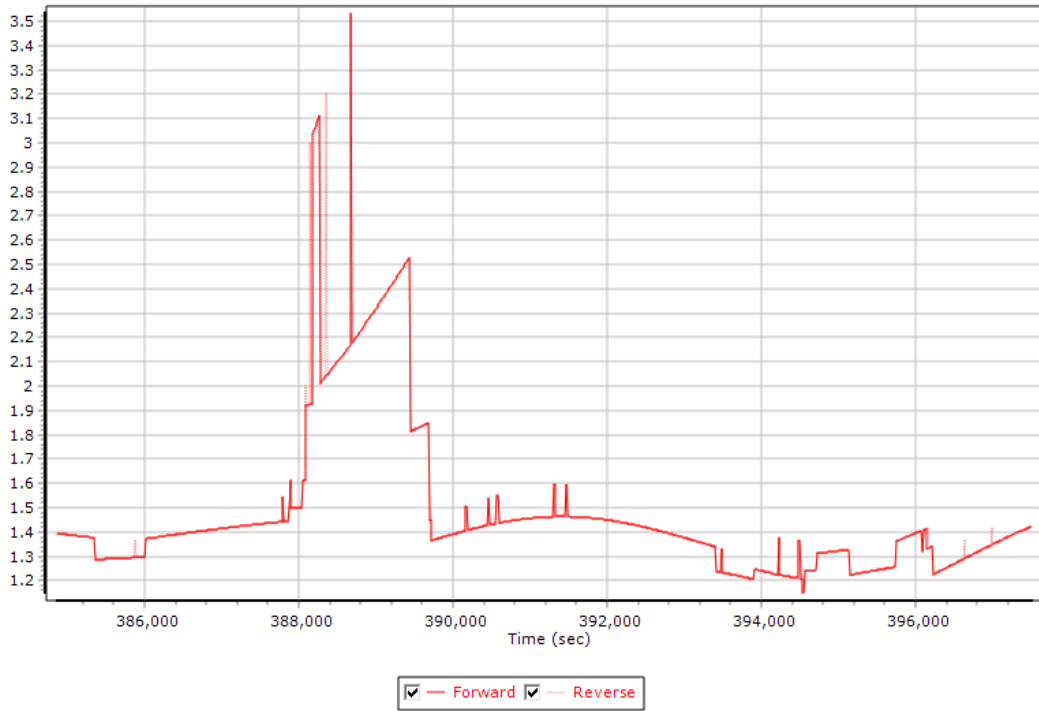




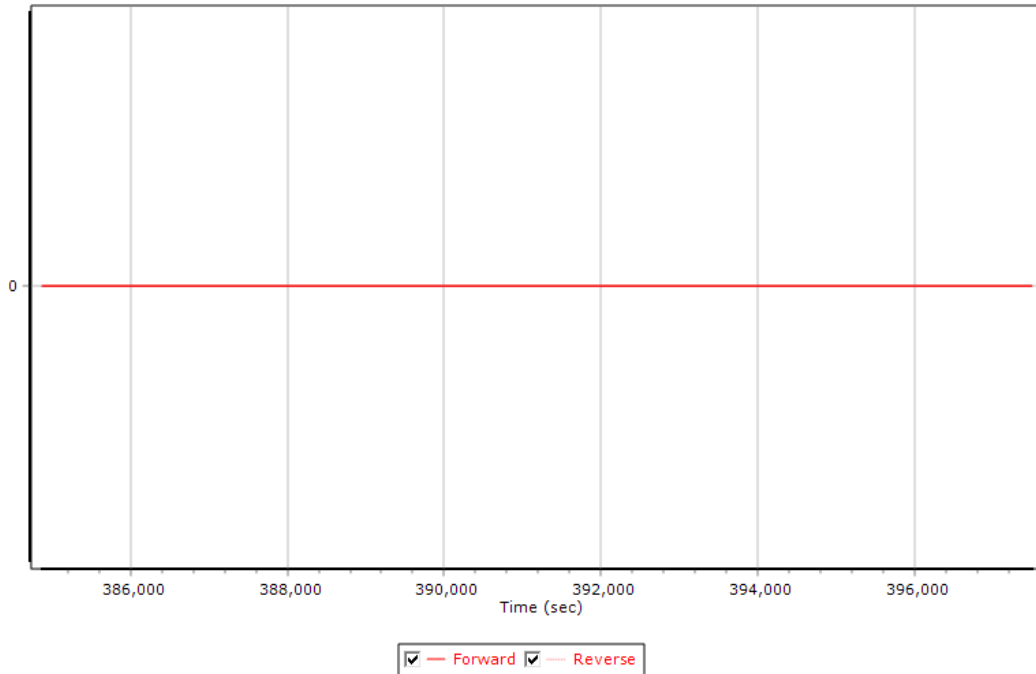
Baseline Length(m)



PDOP

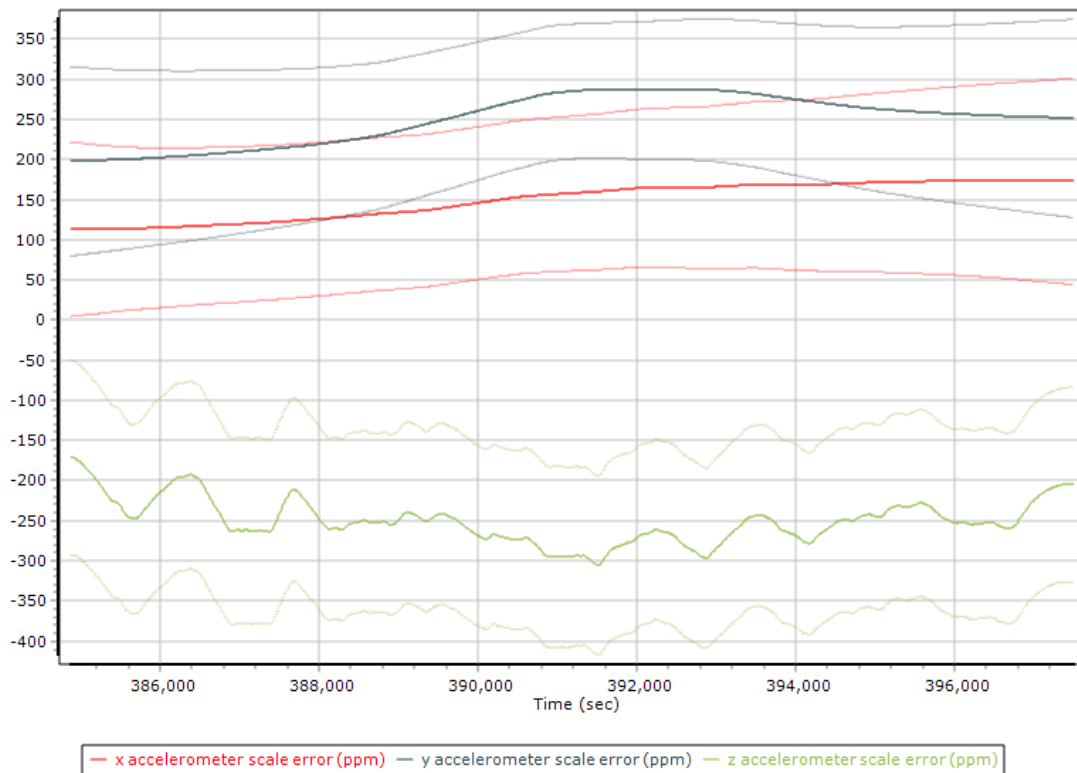
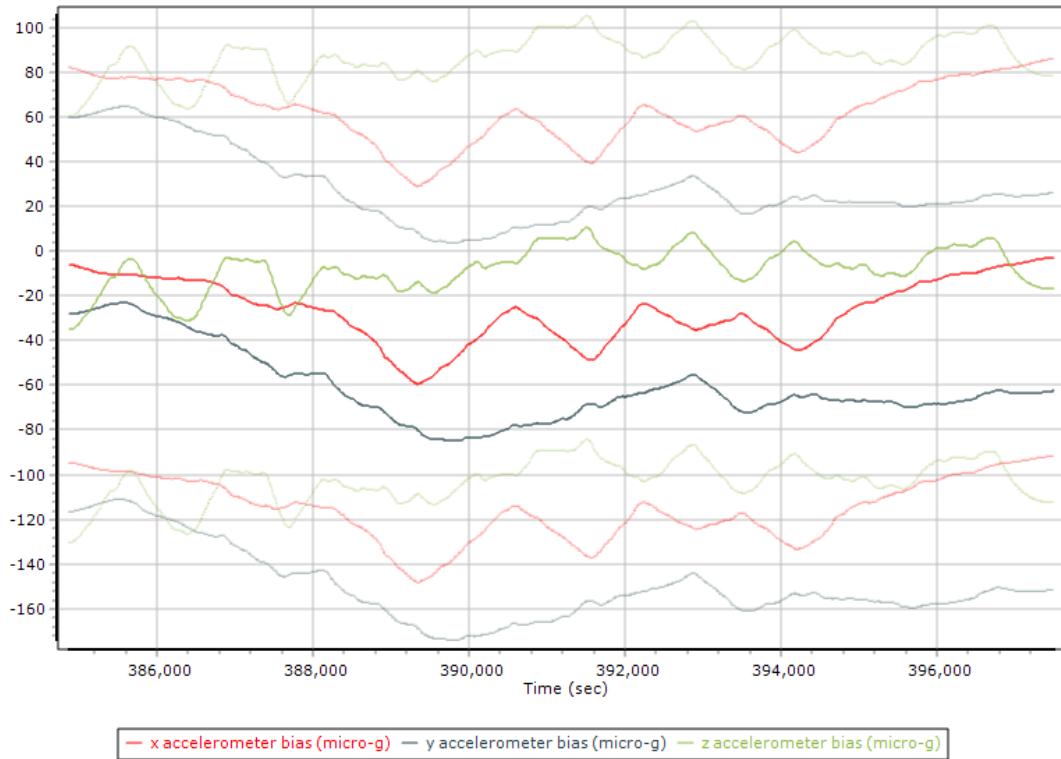


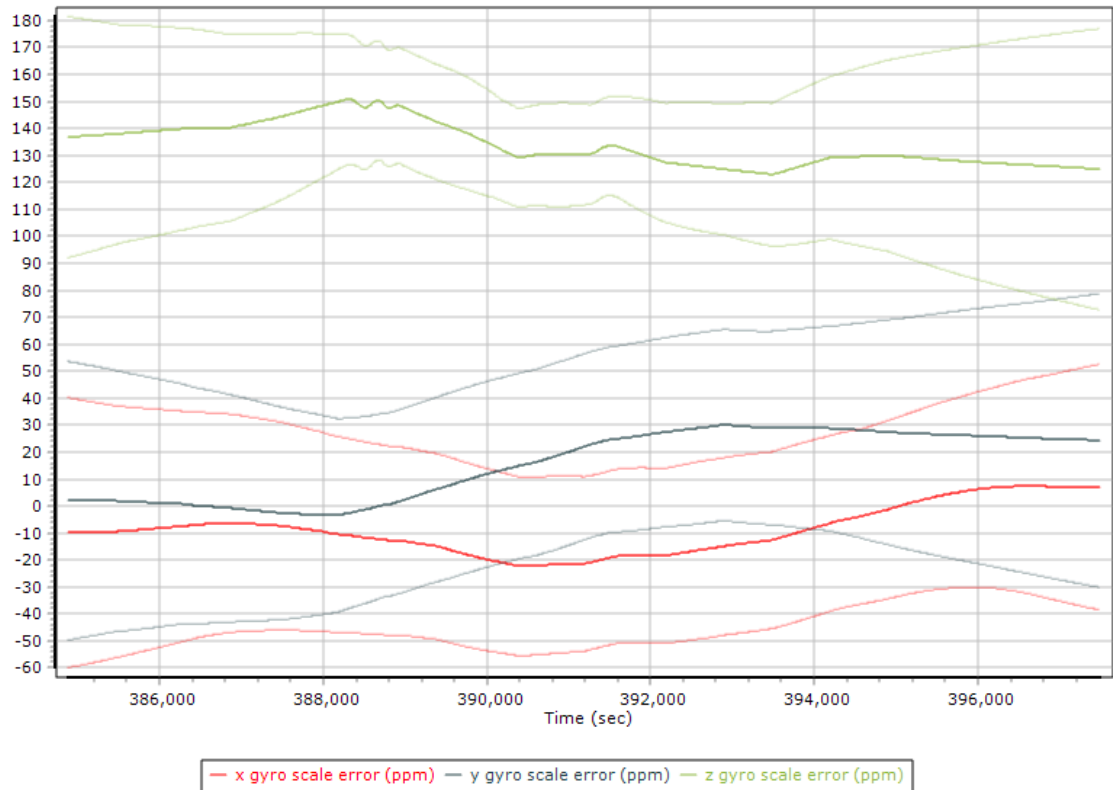
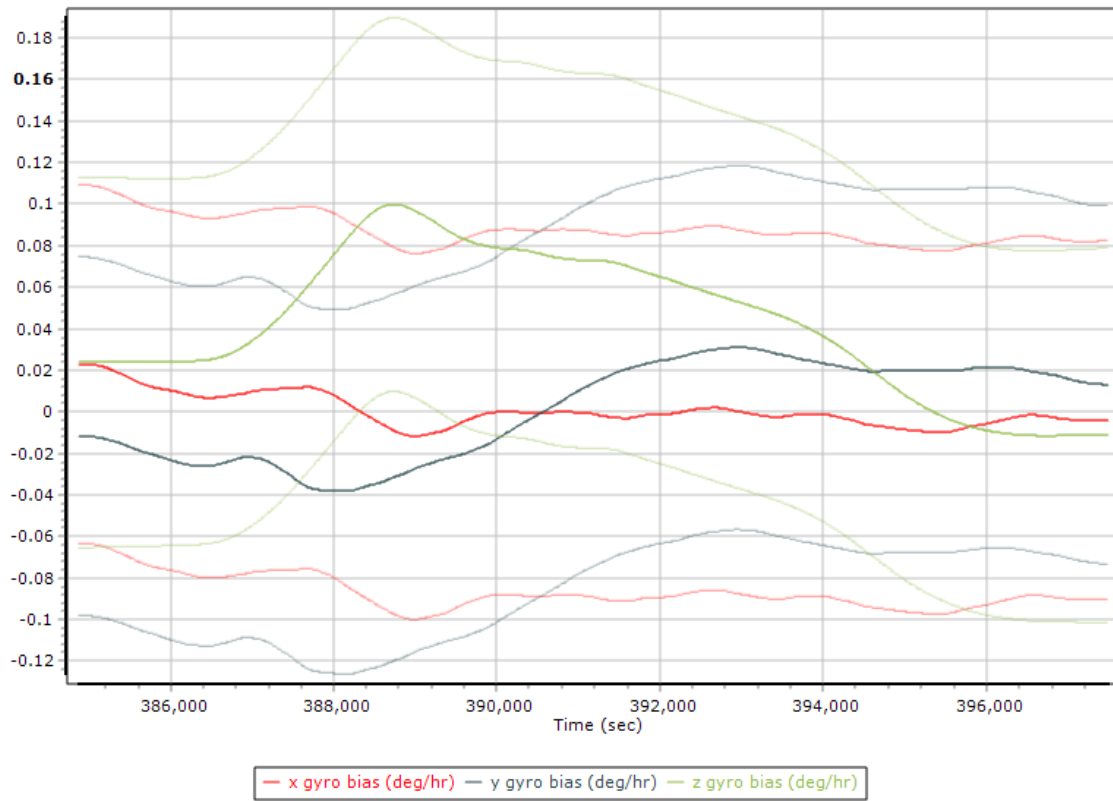
Processing Mode



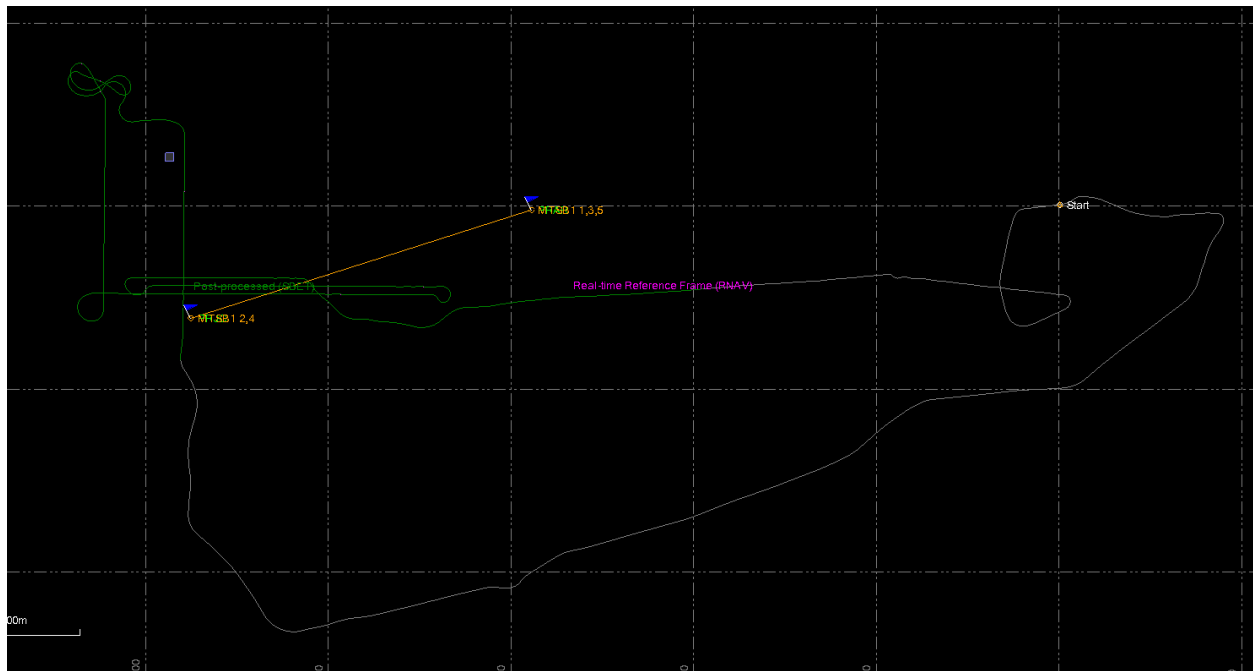
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





RBV18125A



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: -0.037 m	X: 0.000 deg
Y: 0.007 m	Y: 0.000 deg
Z: -0.985 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.

Timing

Start

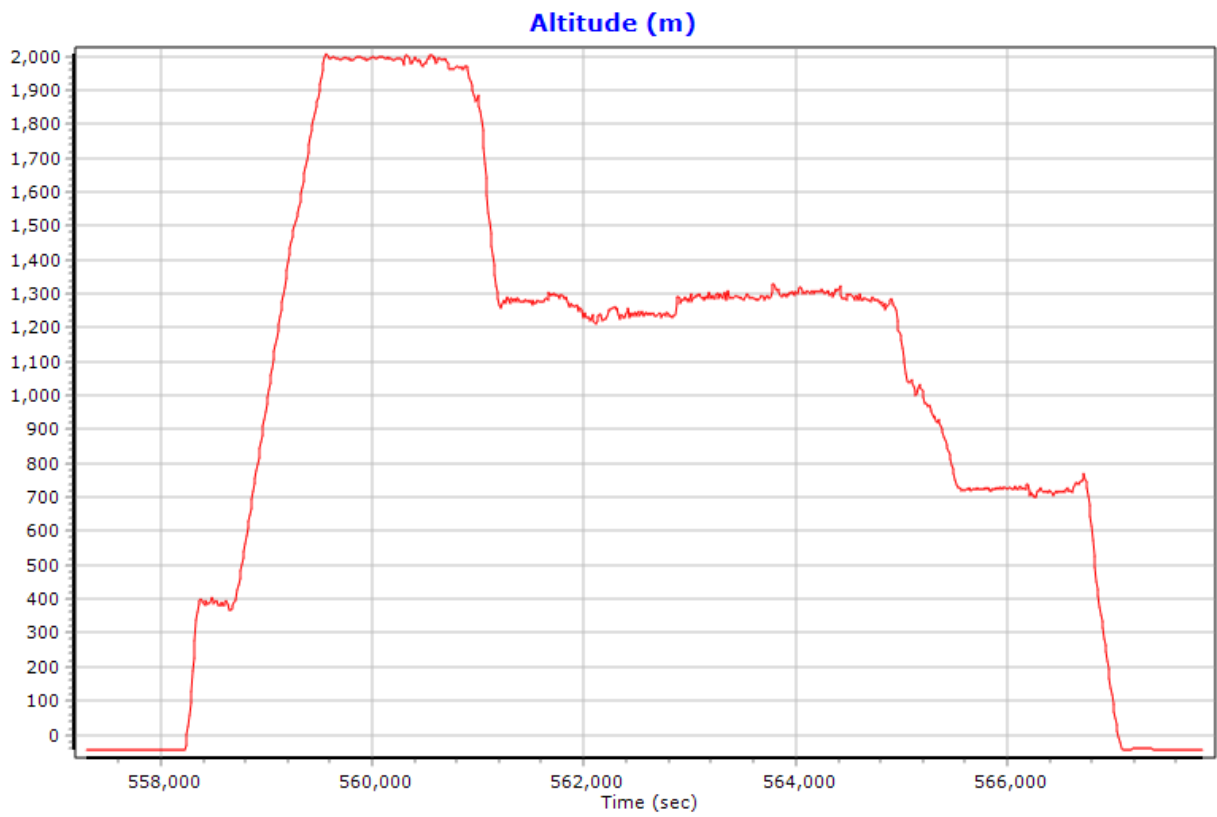
End

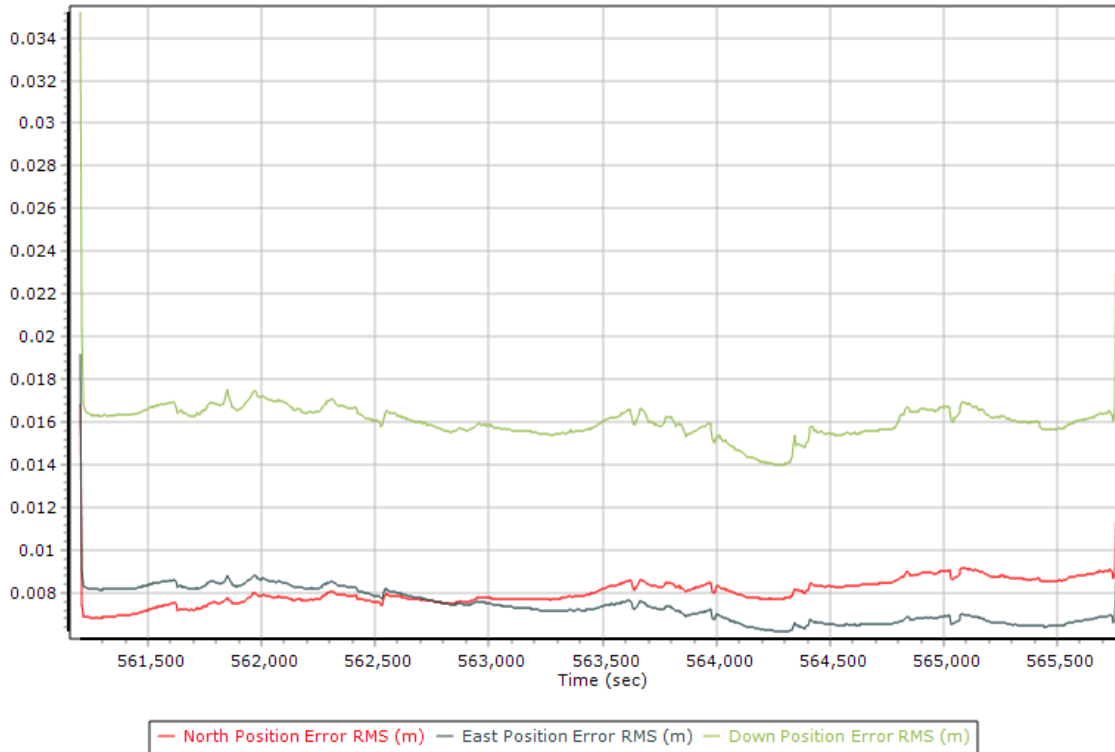
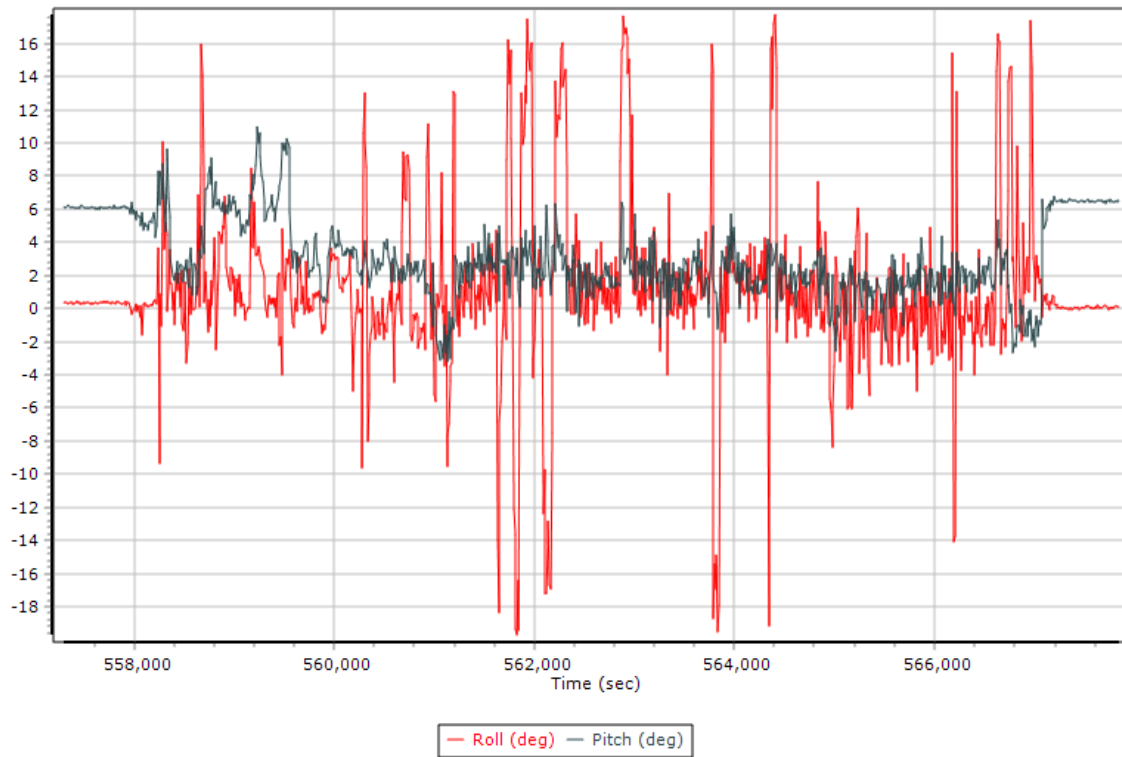
Entire time interval

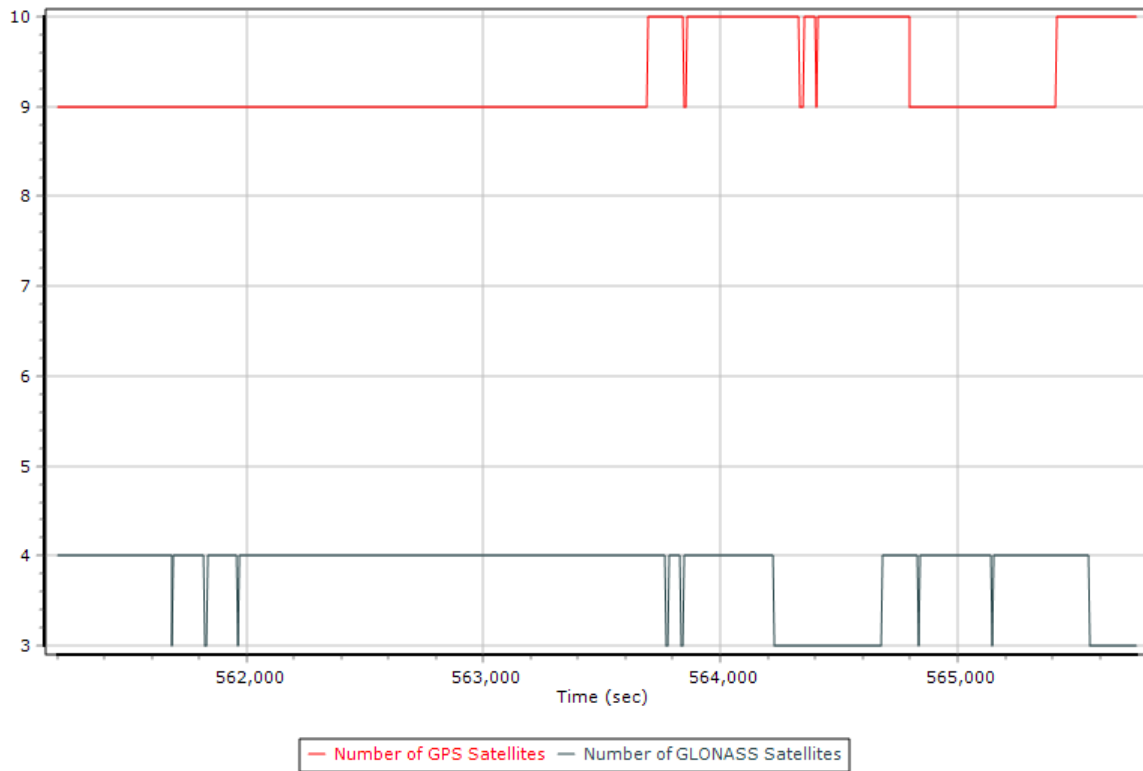
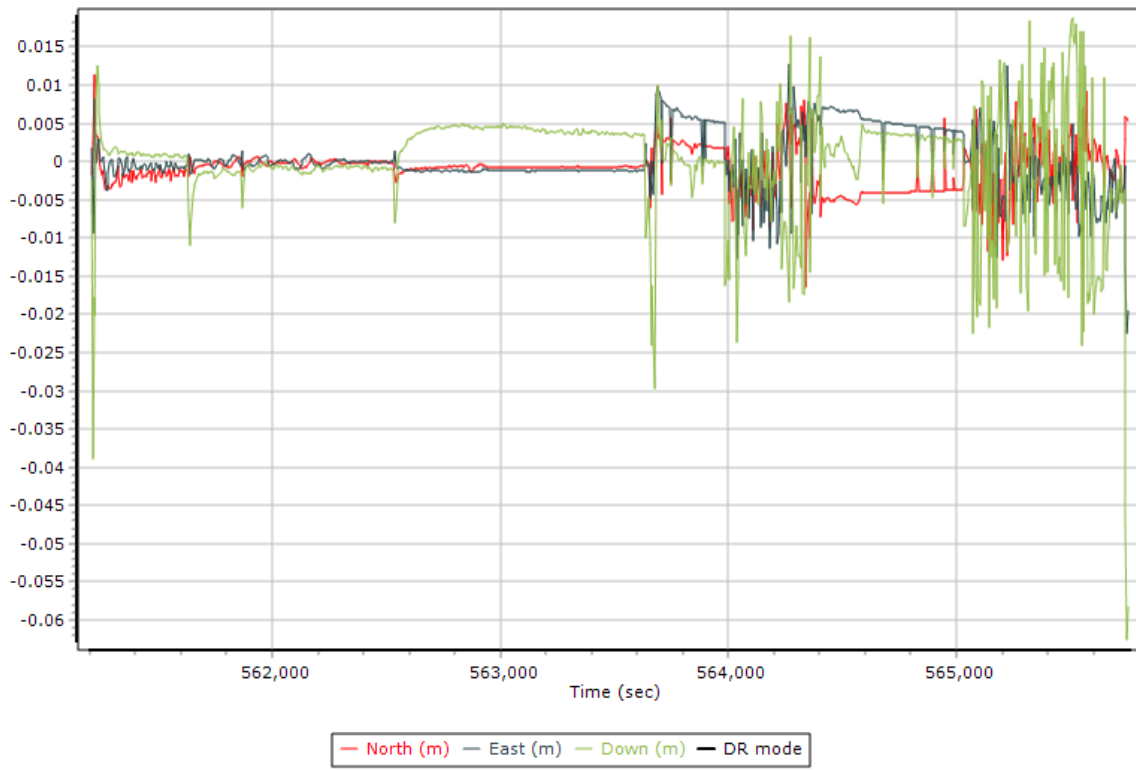
Seconds of start week

UTC Offset

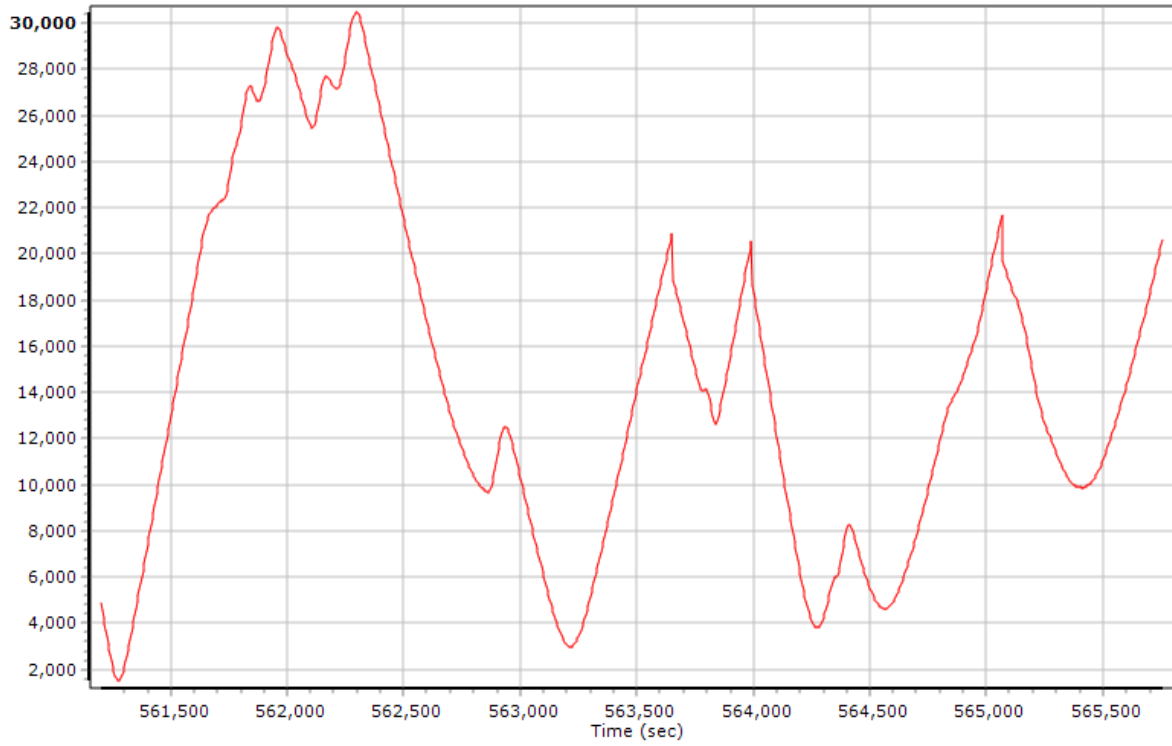
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



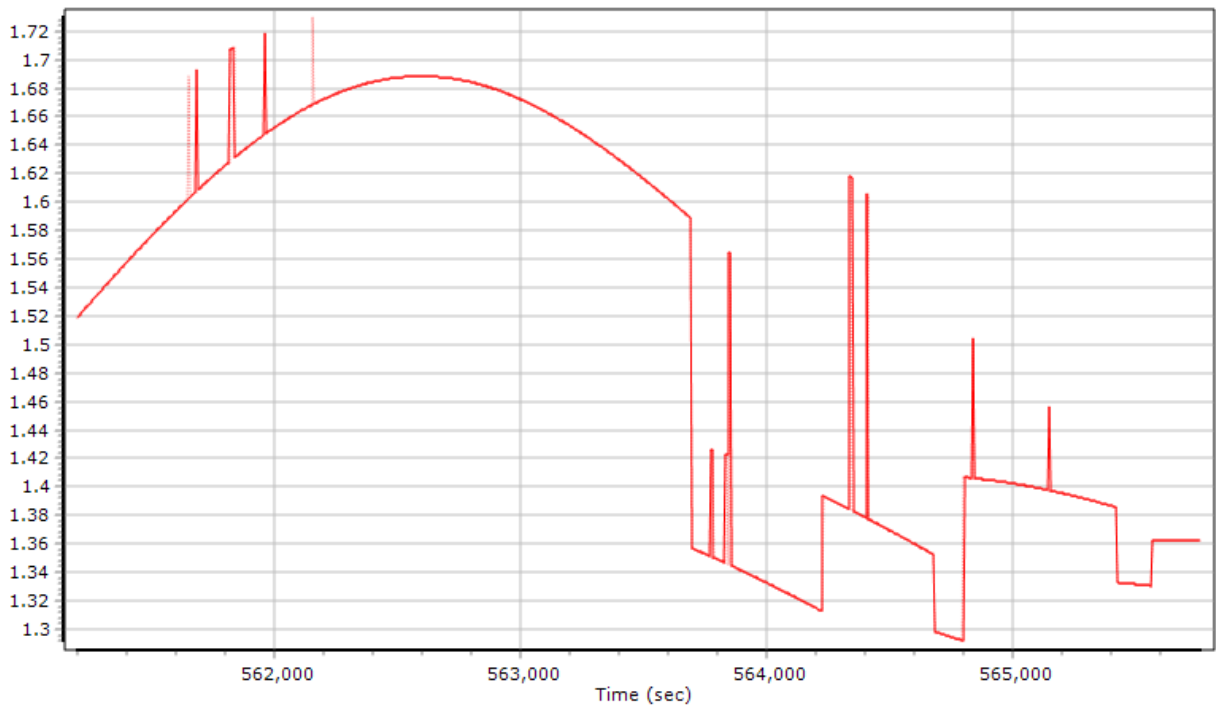




Baseline Length(m)

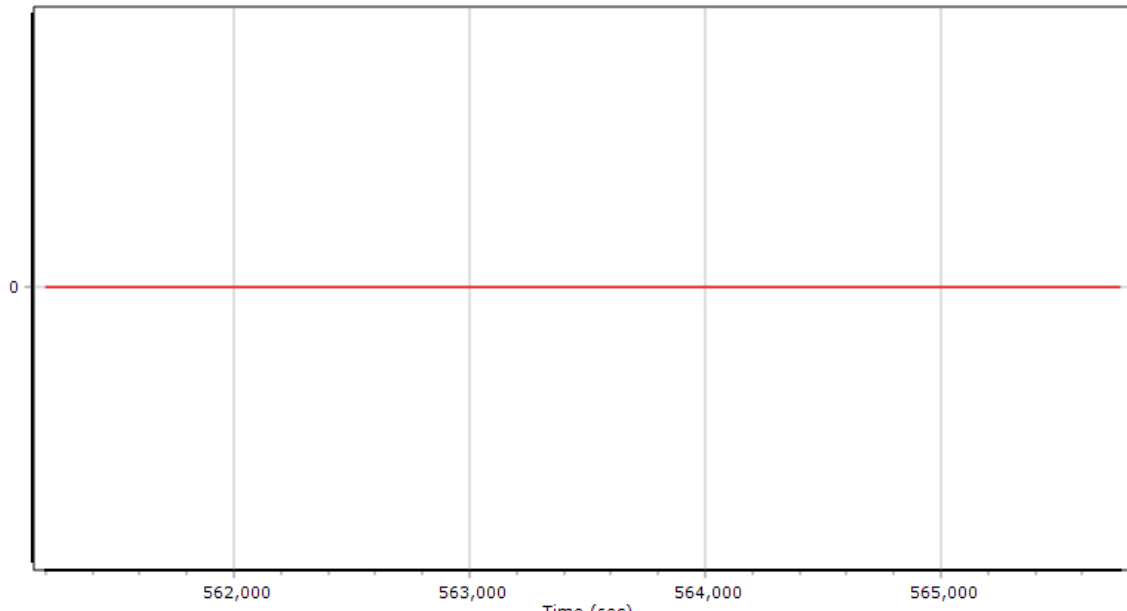


PDOP



Forward Reverse

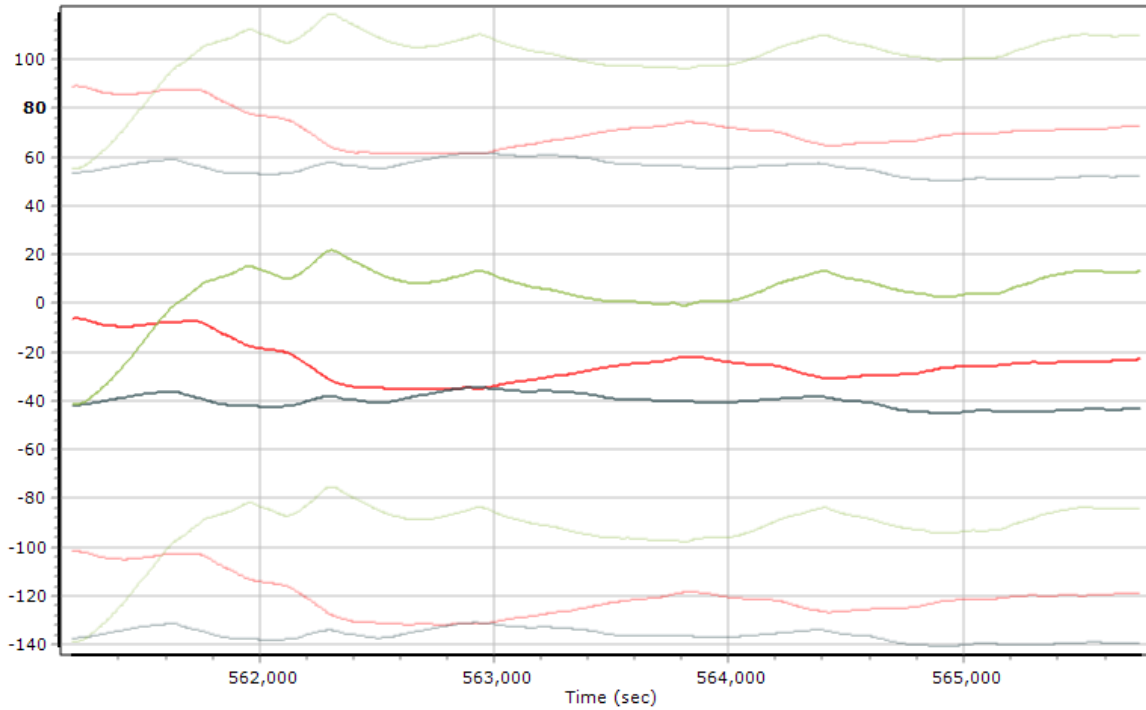
Processing Mode



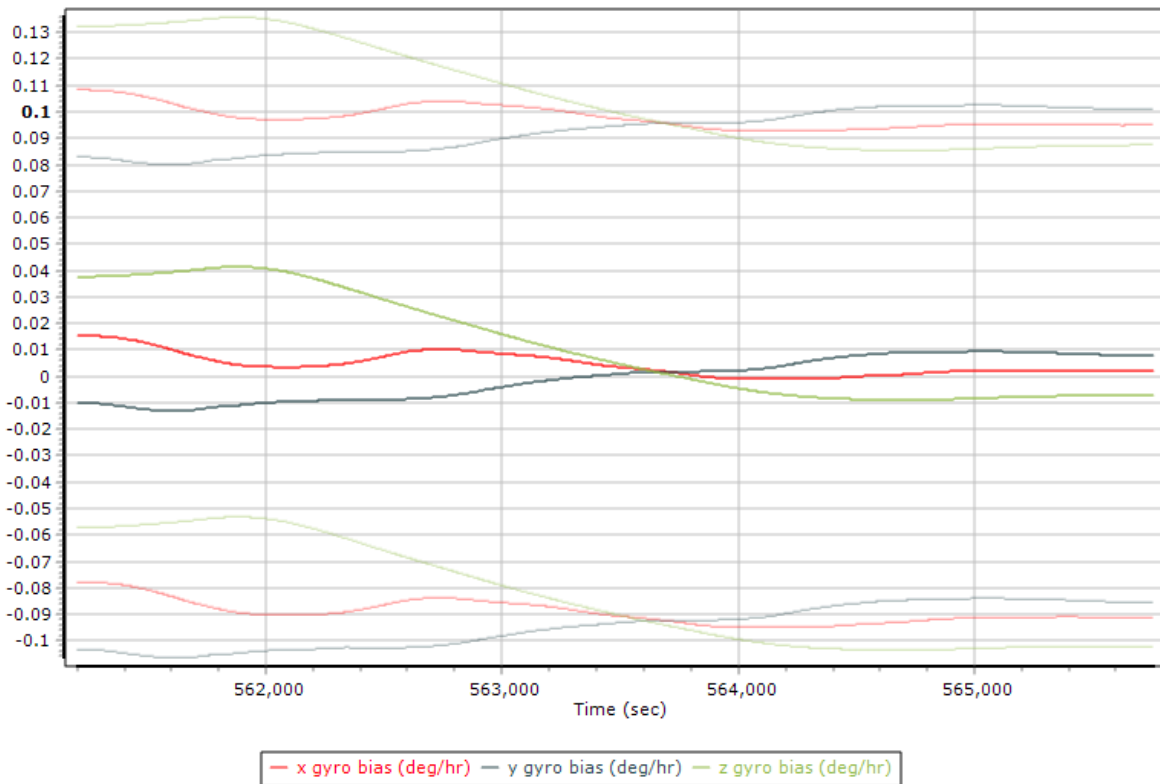
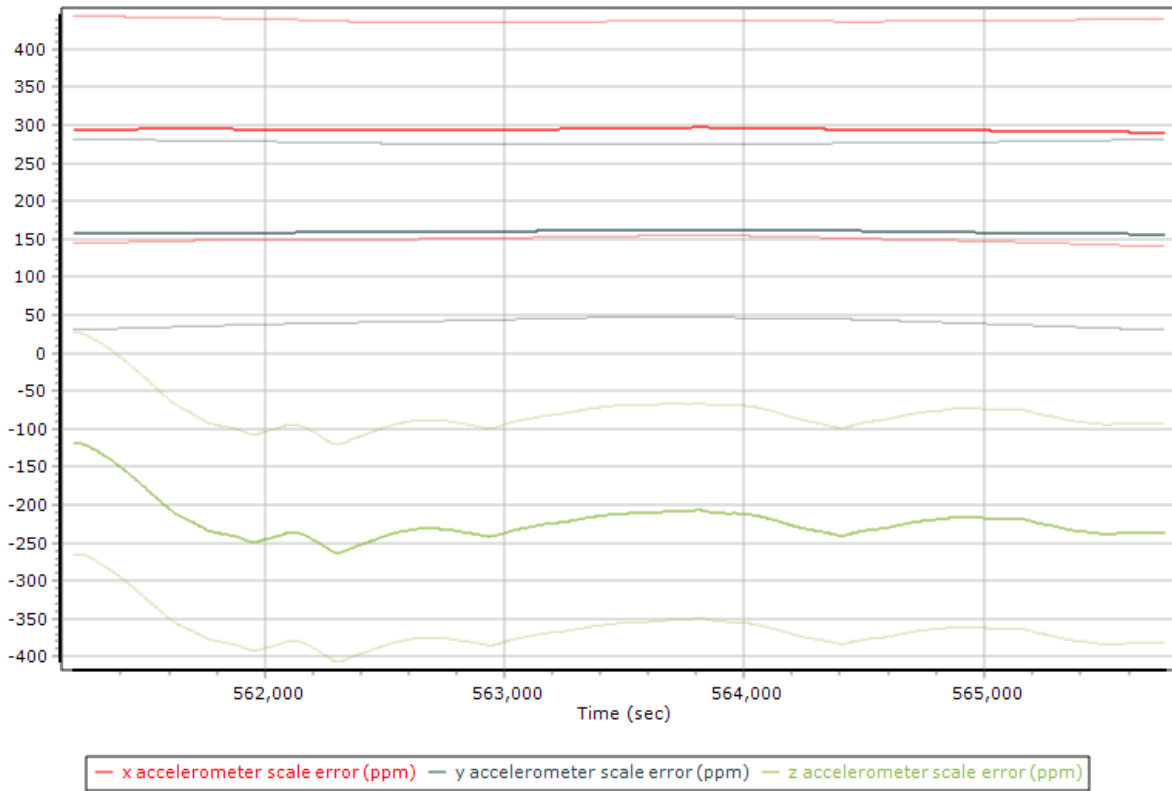
Forward Reverse

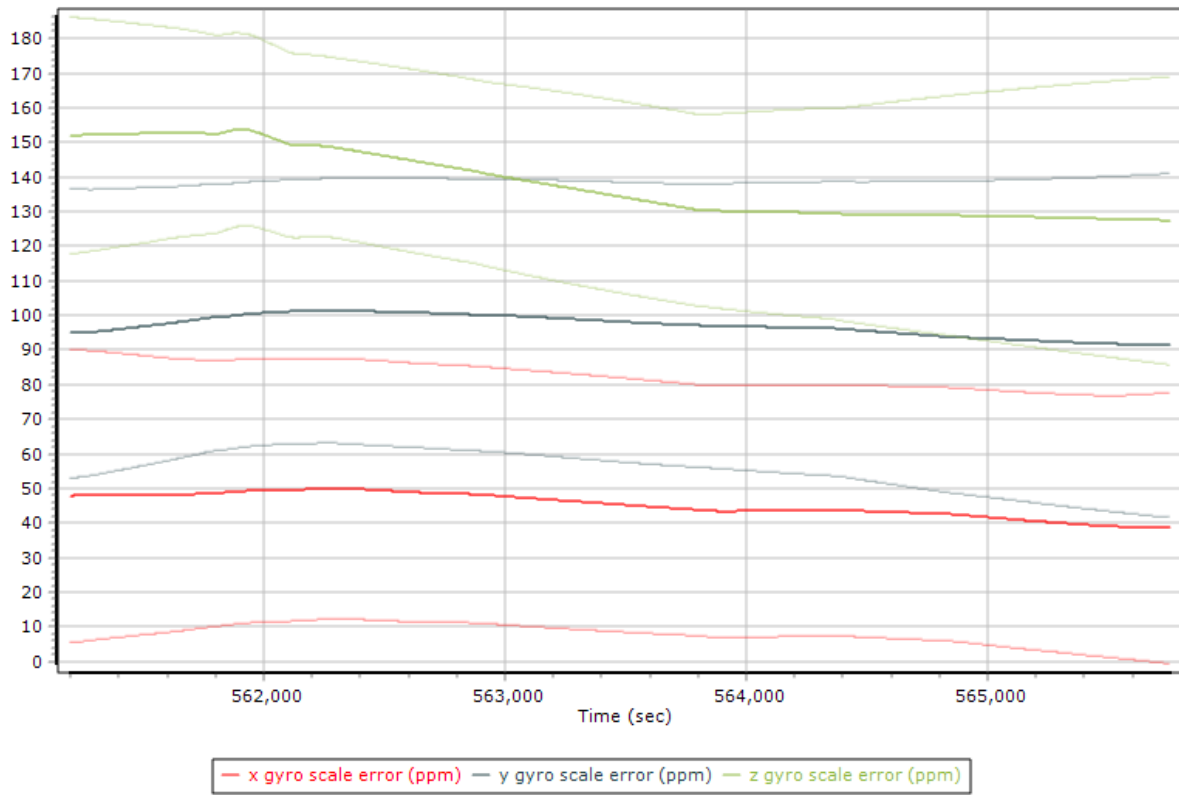
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

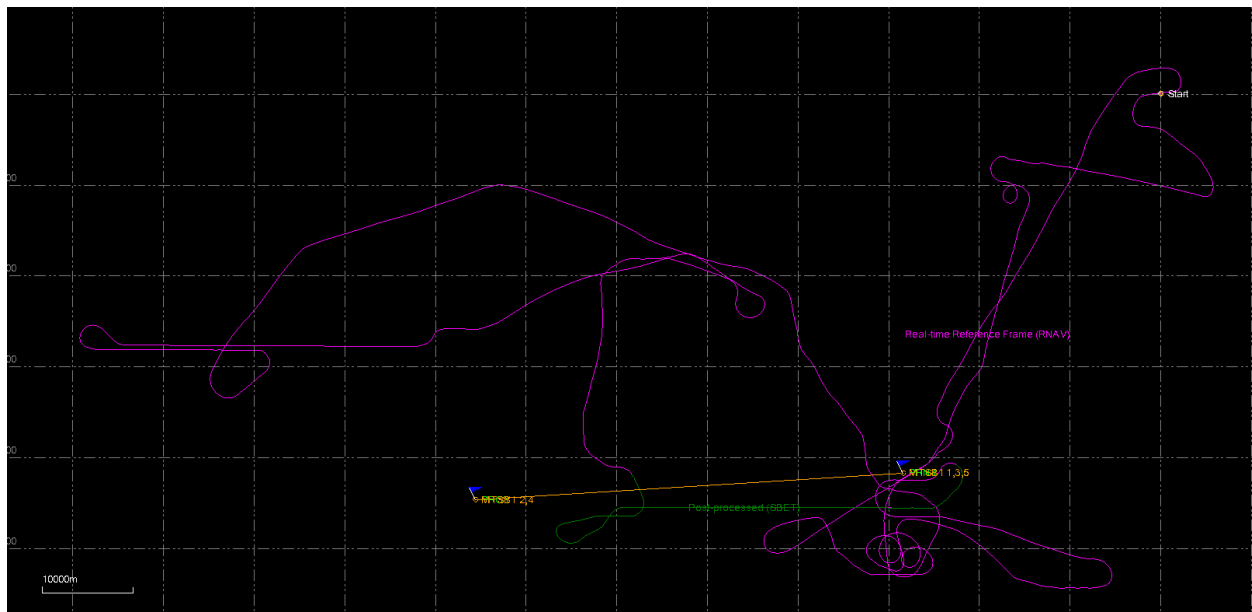


— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)





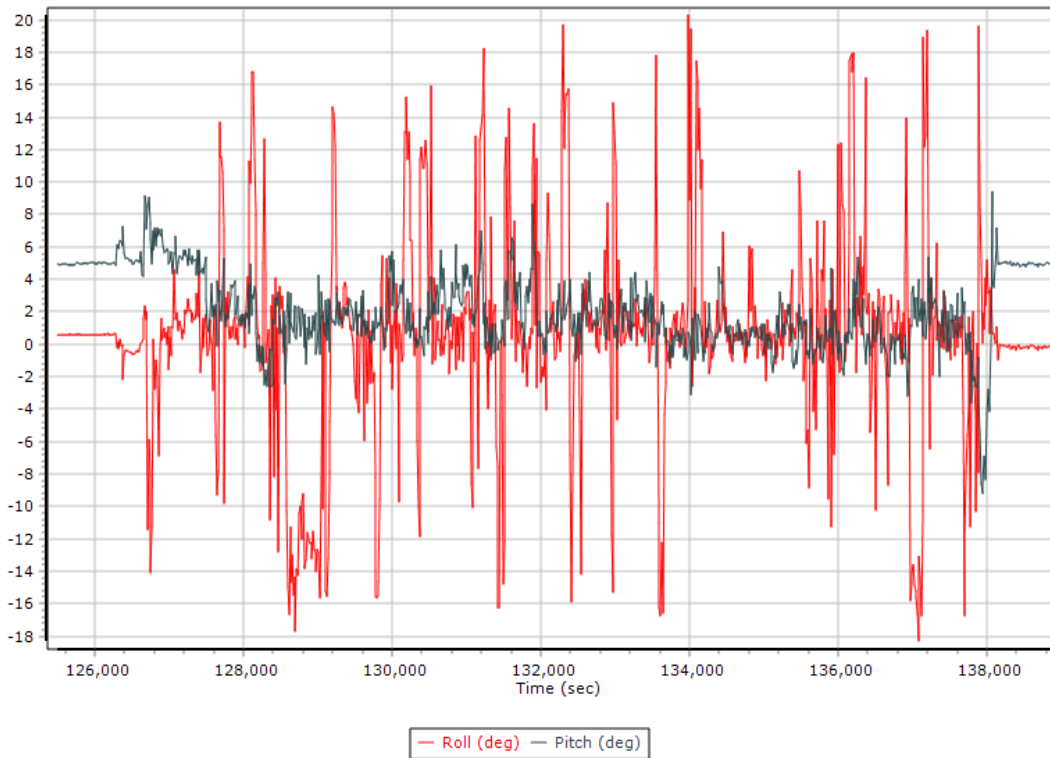
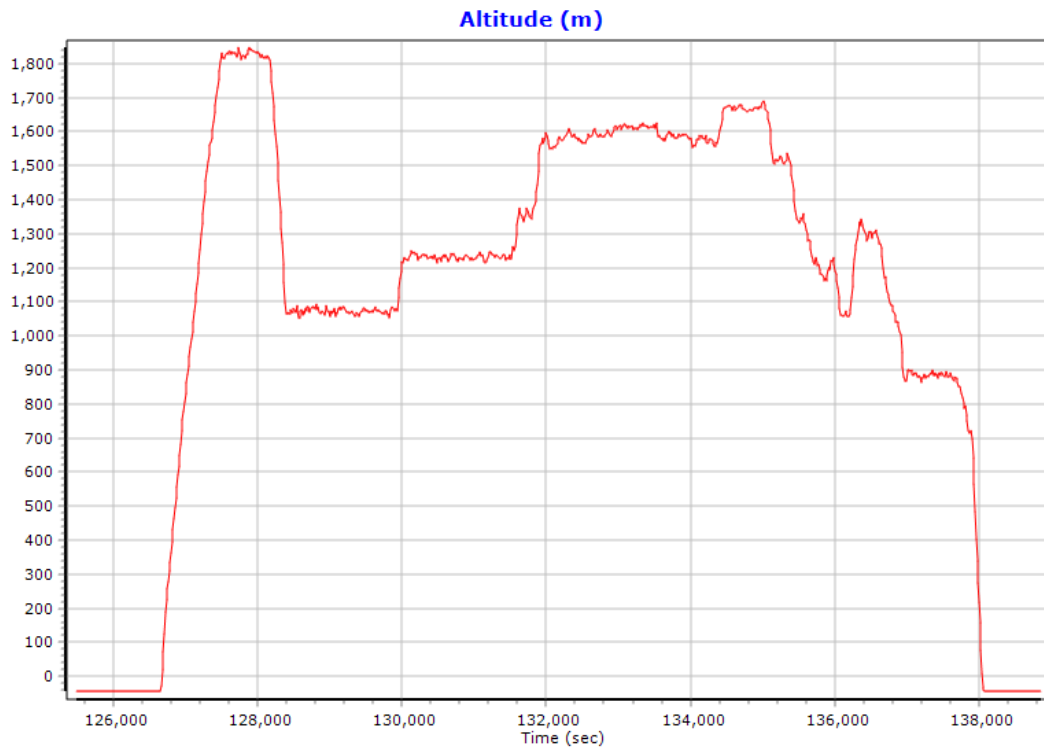
RBV18127A

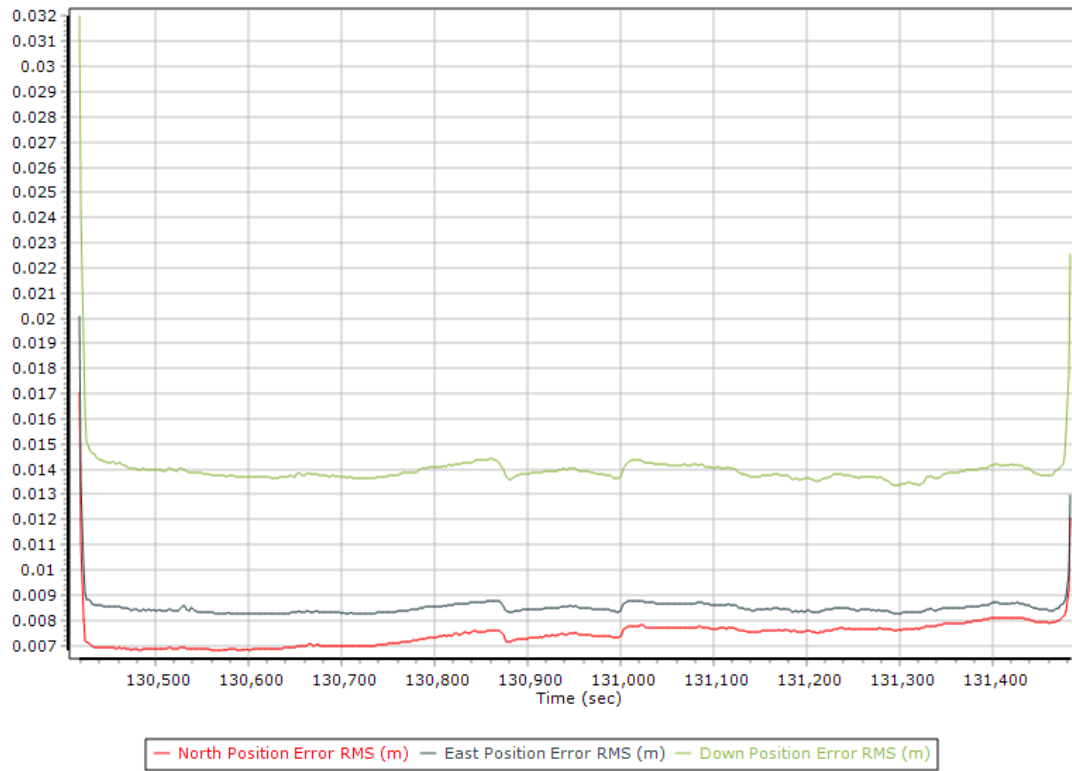


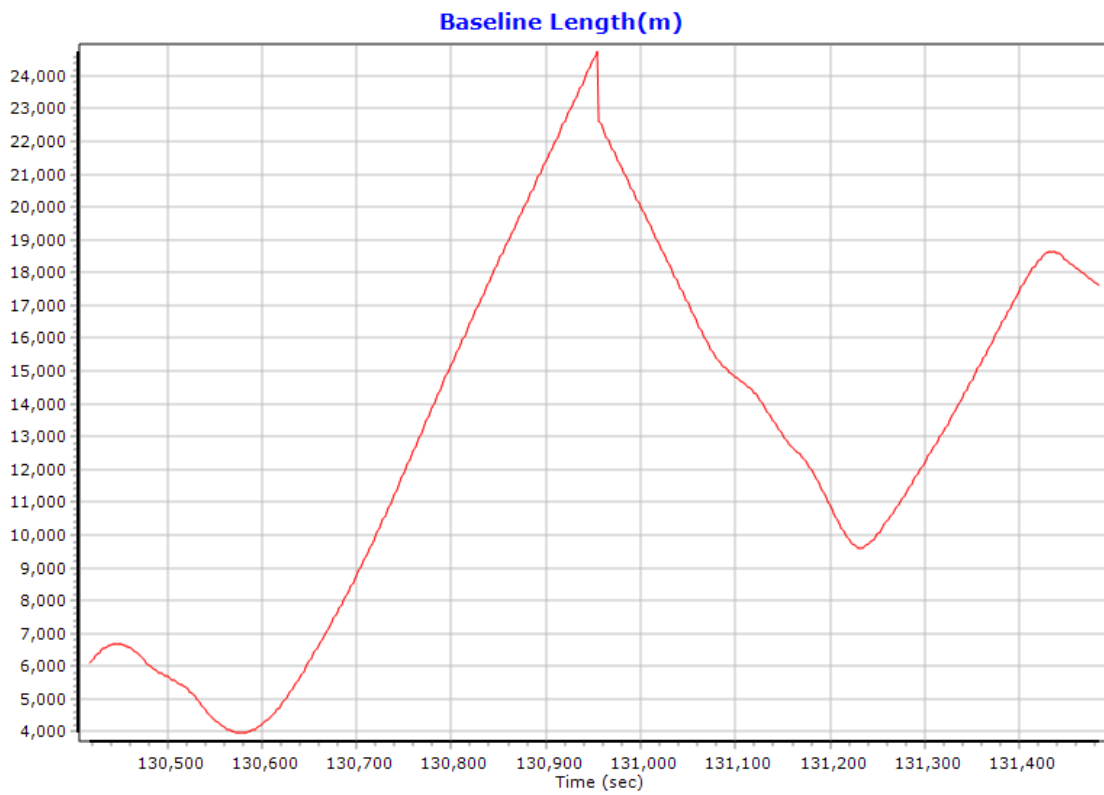
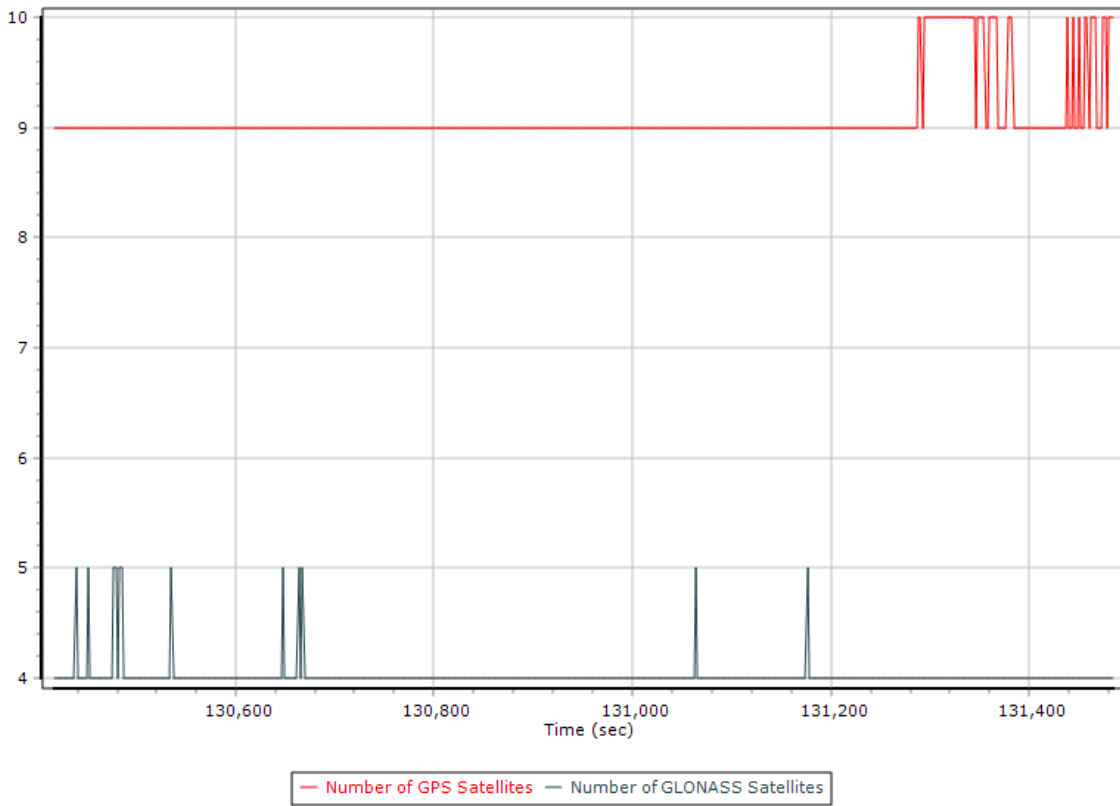
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 deg"/>
Stabilized Mount to Primary GNSS Lever Arm		Aircraft to Stabilized Mount Mounting Angles	
X	<input type="text" value="-0.037 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="0.007 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.985 m"/>	Z	<input type="text" value="0.000 deg"/>
Standard Deviation	<input type="range" value="0.3"/>		
	<3cm 10cm 50cm 1m 10m		

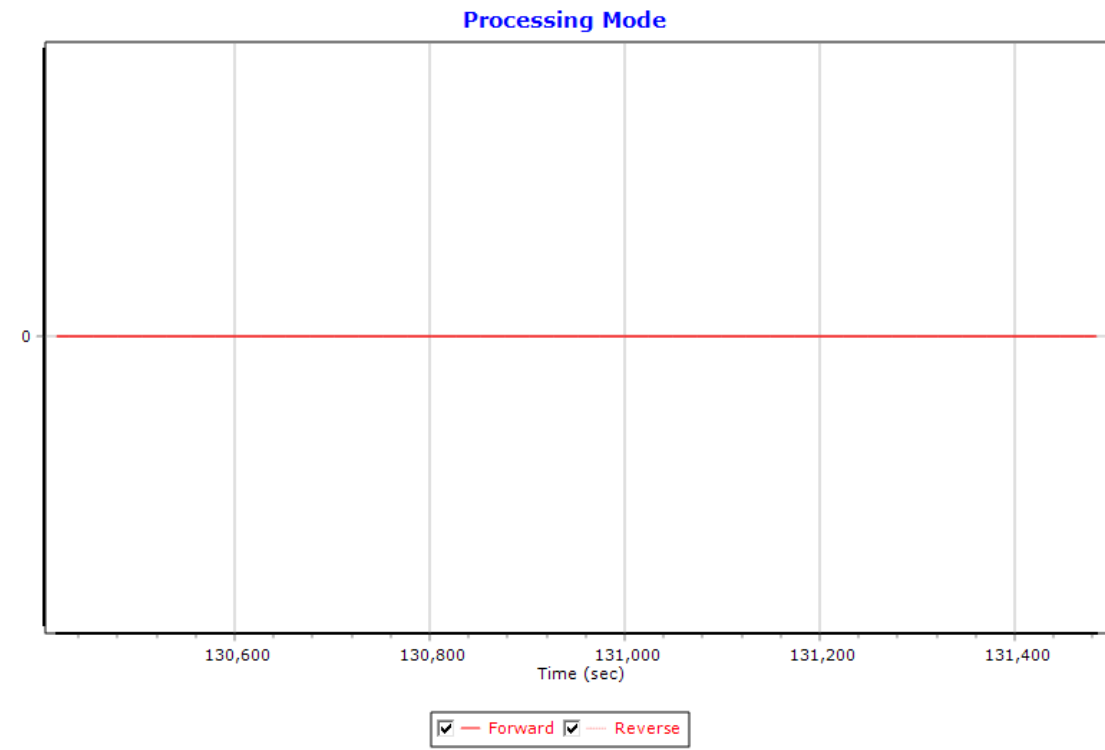
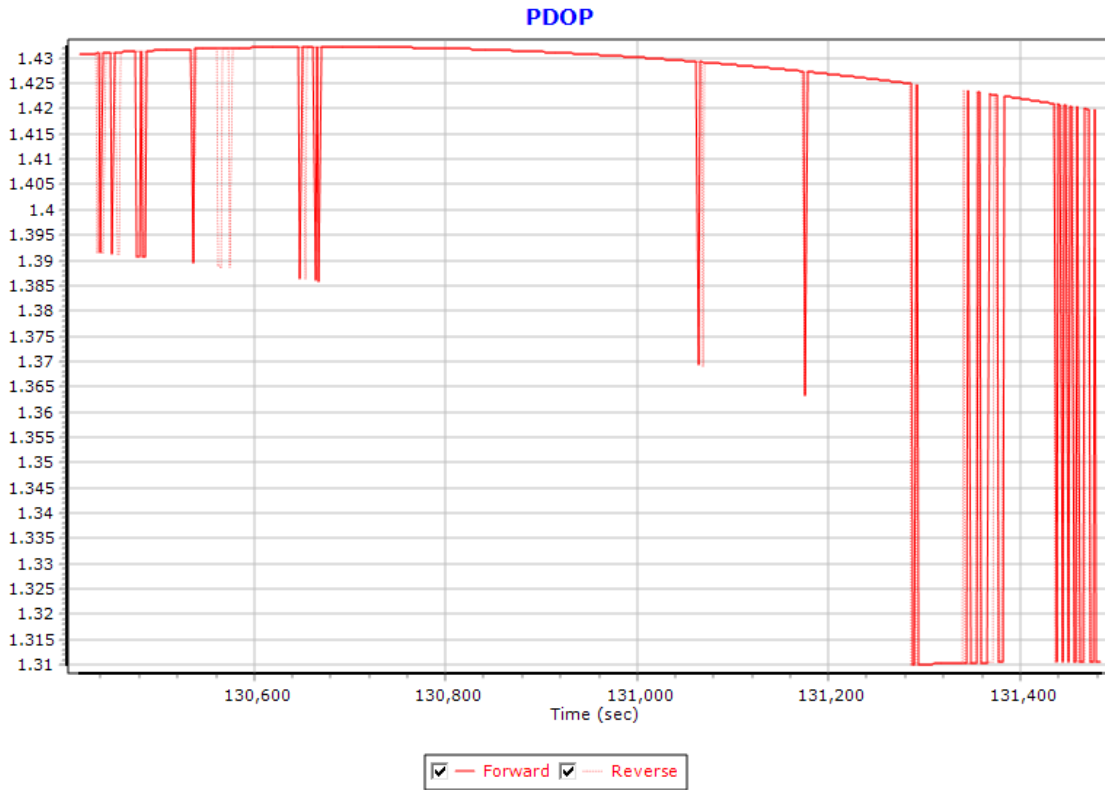
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

Timing									
Start	<input type="text" value="125496.000"/>								
End	<input type="text" value="138857.000"/>								
<input checked="" type="checkbox"/> Entire time interval									
<input checked="" type="checkbox"/> Seconds of start week									
UTC Offset	<input type="text" value="18.000"/>								
<table border="1"><thead><tr><th>Data</th><th>Incr. (sec)</th></tr></thead><tbody><tr><td>Output Record</td><td>0.005000</td></tr><tr><td>IMU</td><td>0.005000</td></tr><tr><td>Primary GNSS</td><td>1.000000</td></tr></tbody></table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000	<input type="button" value="^"/> <input type="button" value="v"/>
Data	Incr. (sec)								
Output Record	0.005000								
IMU	0.005000								
Primary GNSS	1.000000								



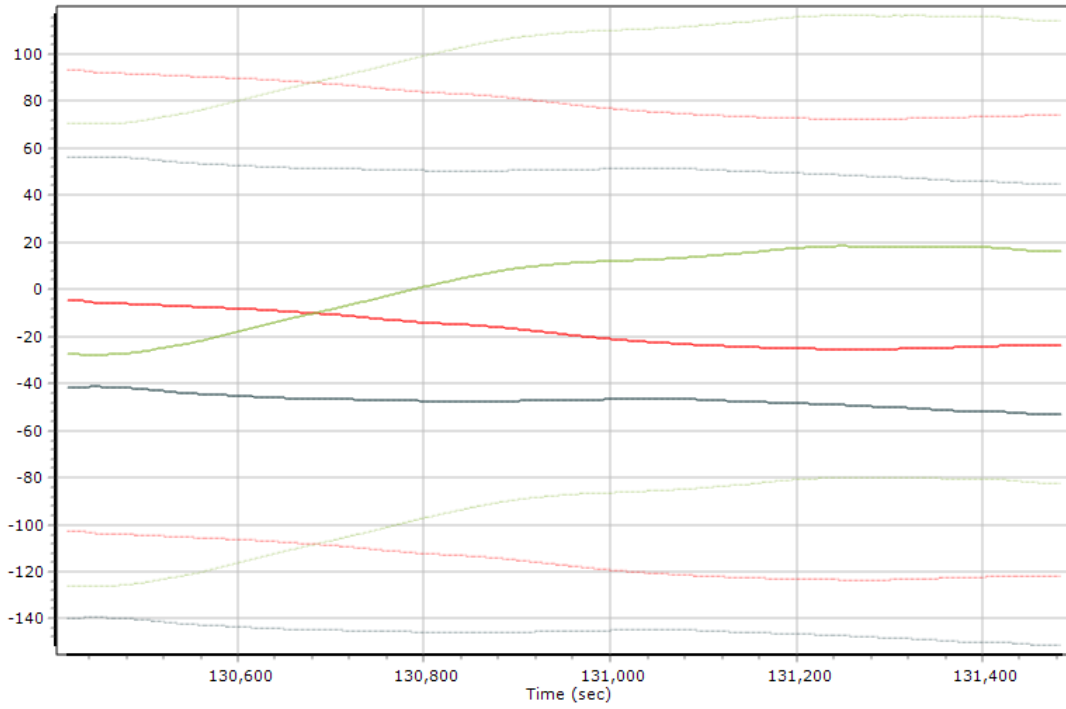




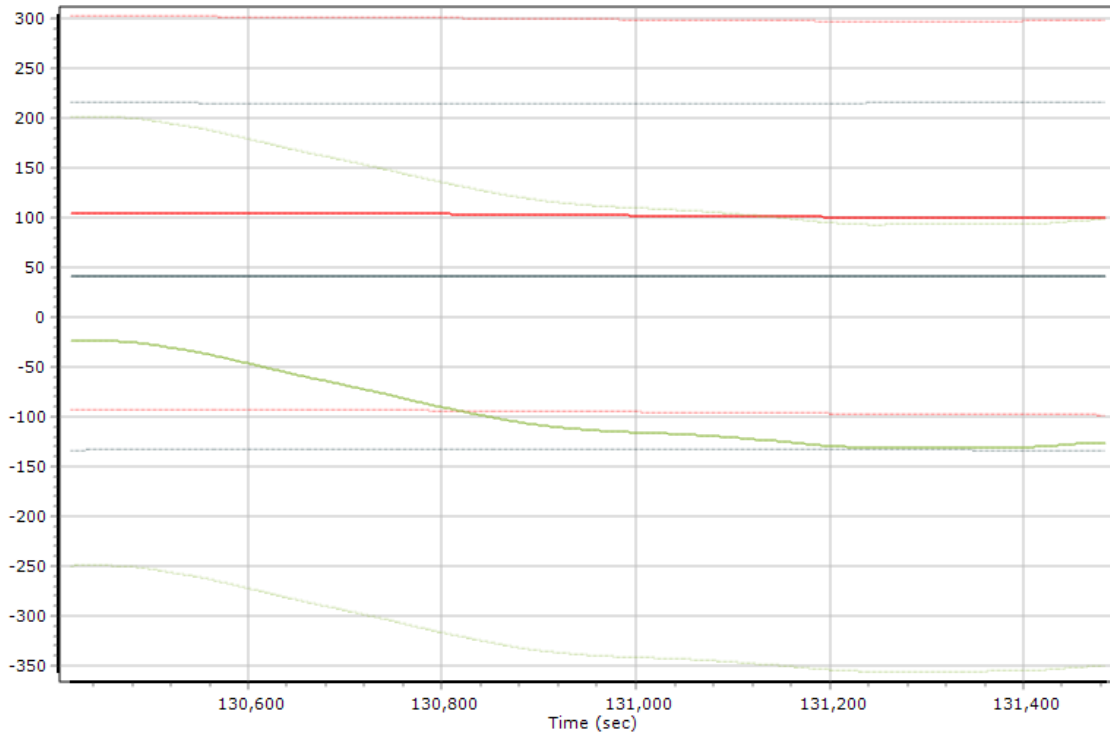


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

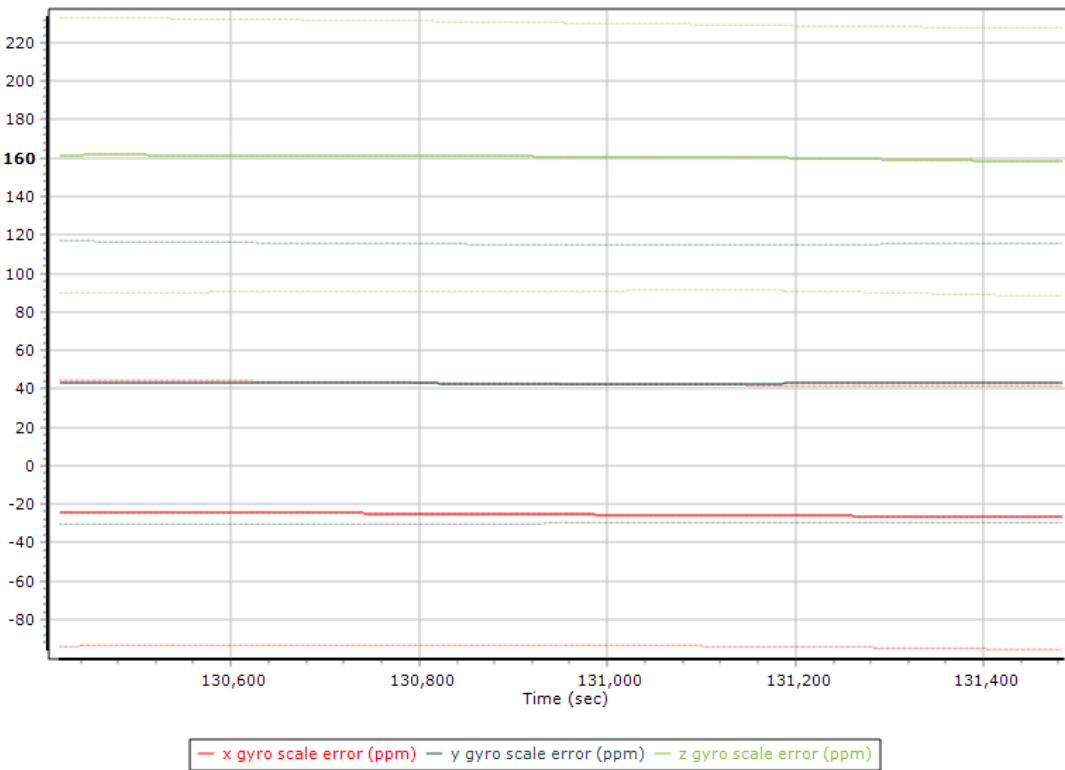
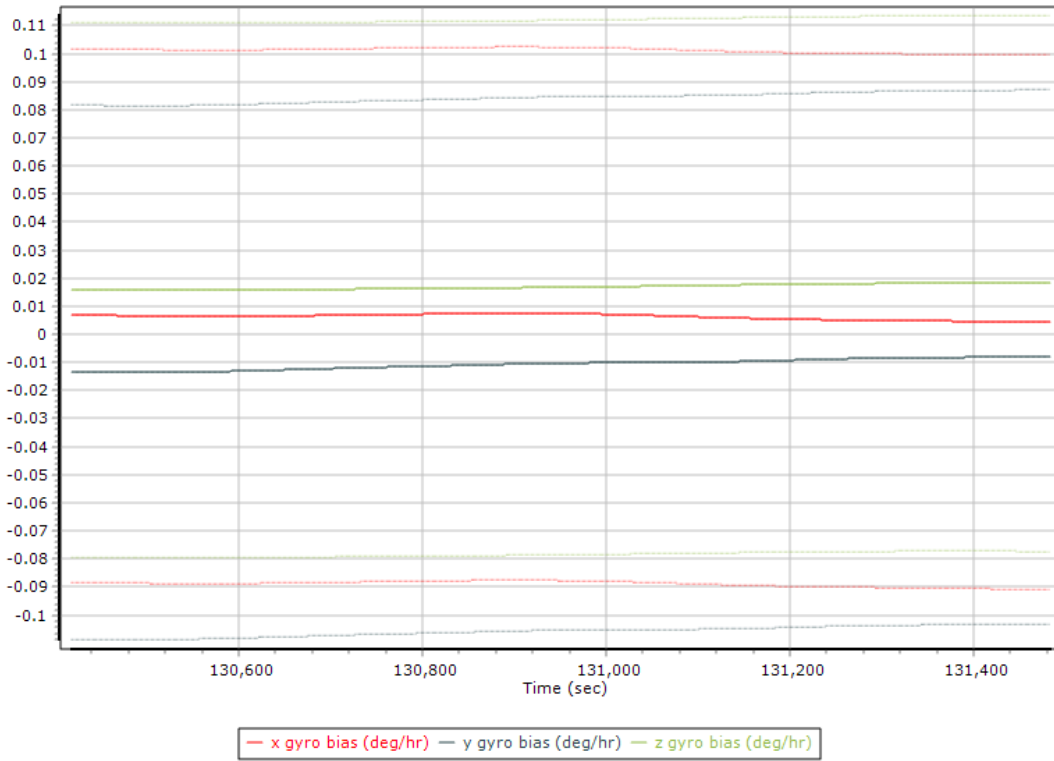
Sensor Errors



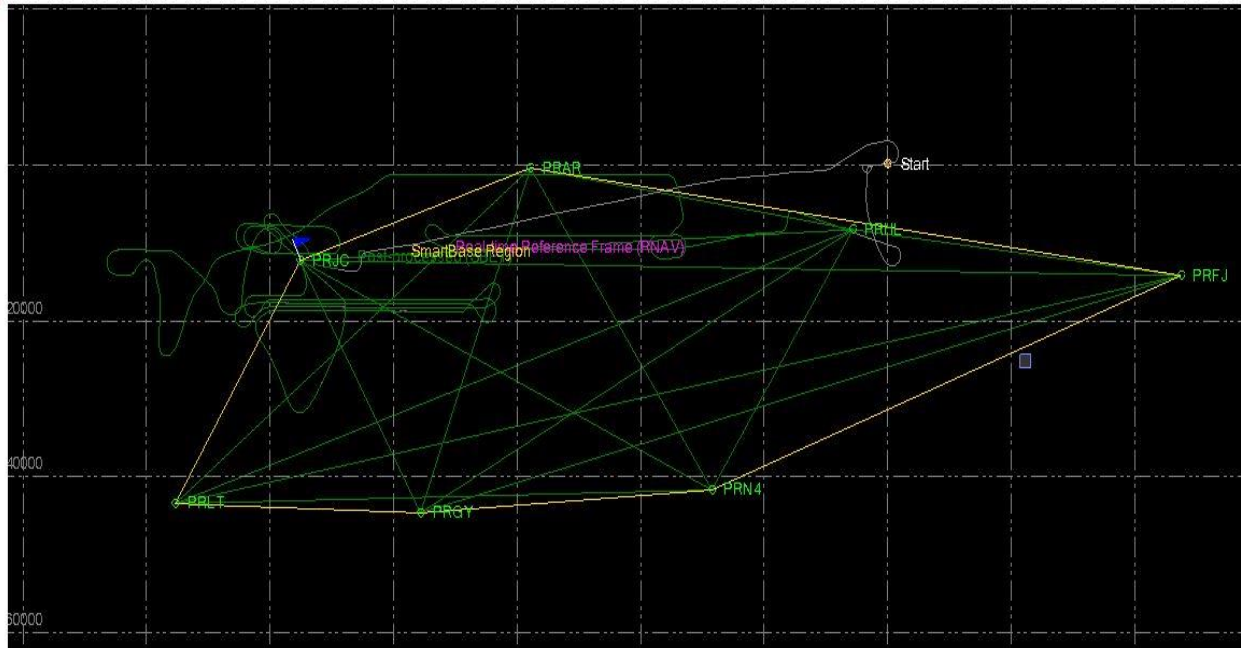
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)



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



RBV18127B



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

Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.037 m	0.007 m	-0.985 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	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: 154137.325

End: 164247.717

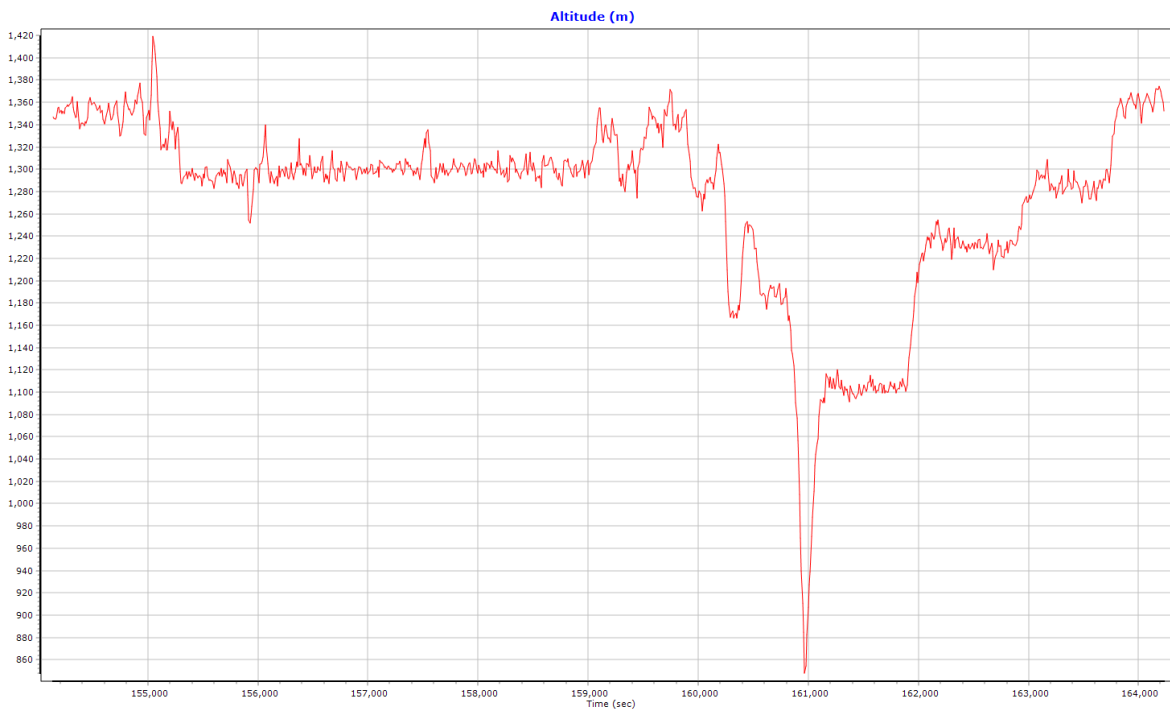
Entire time interval

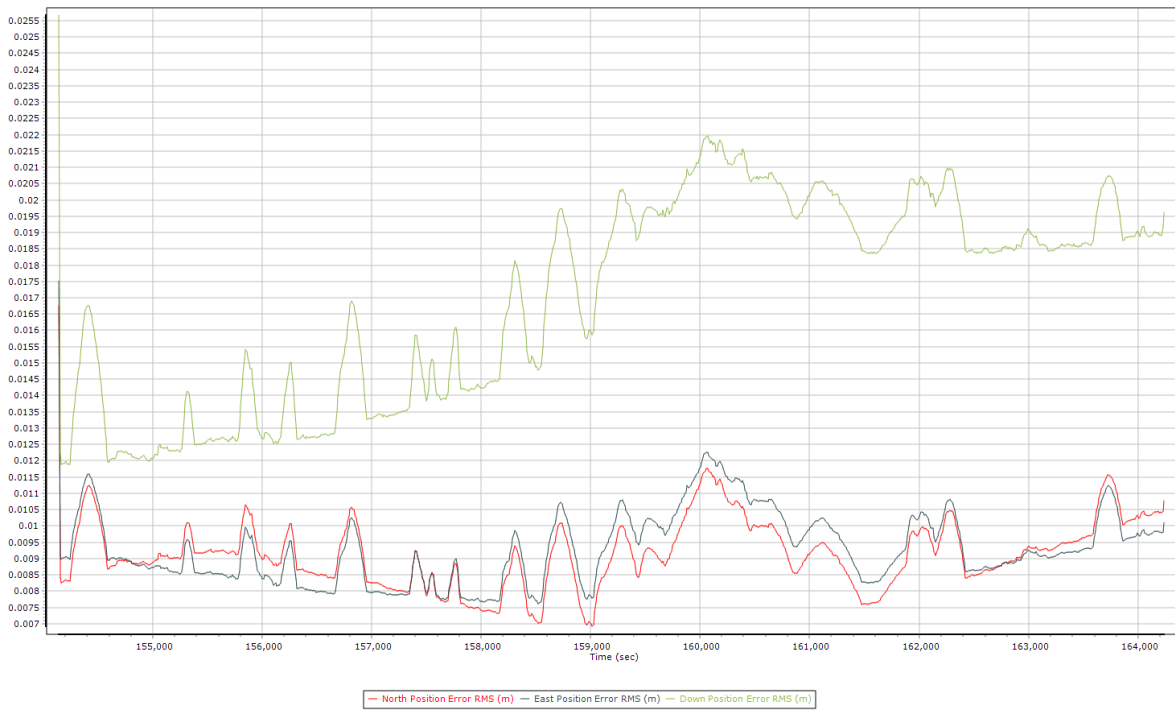
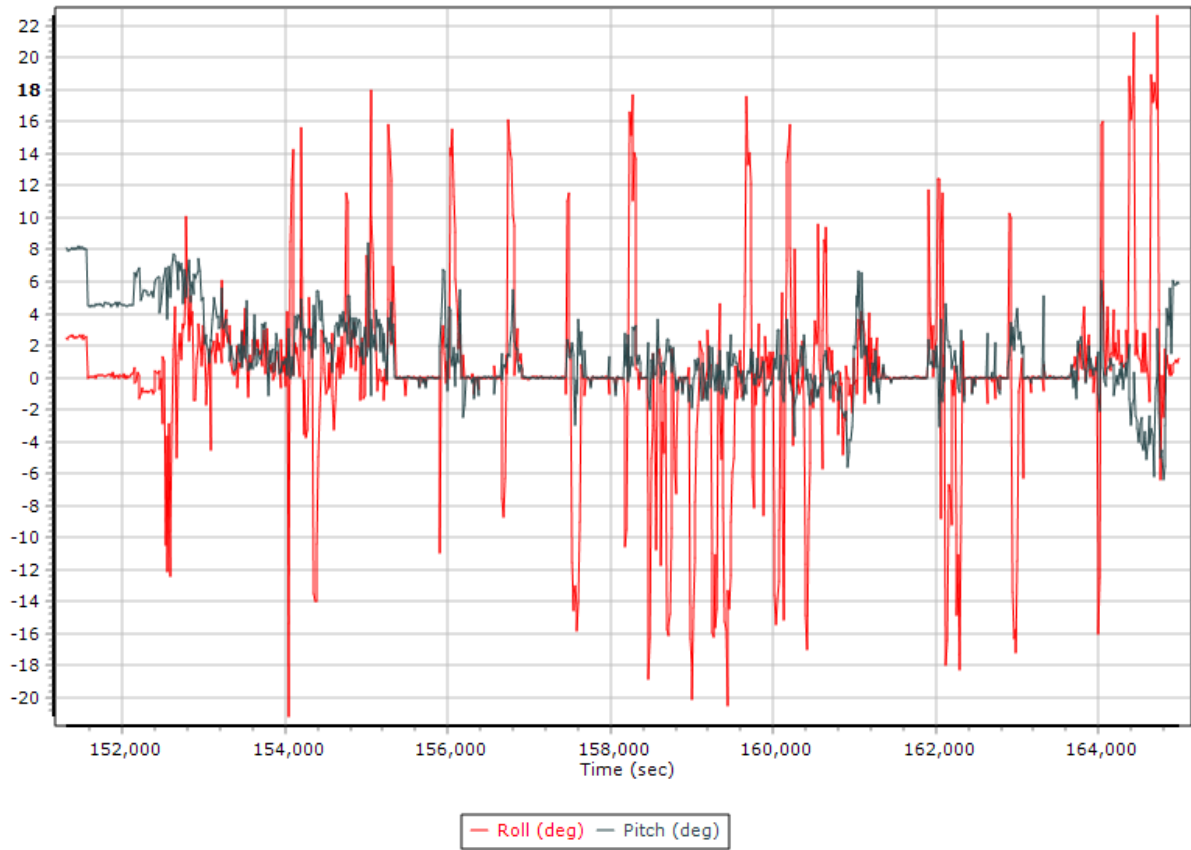
Seconds of start week

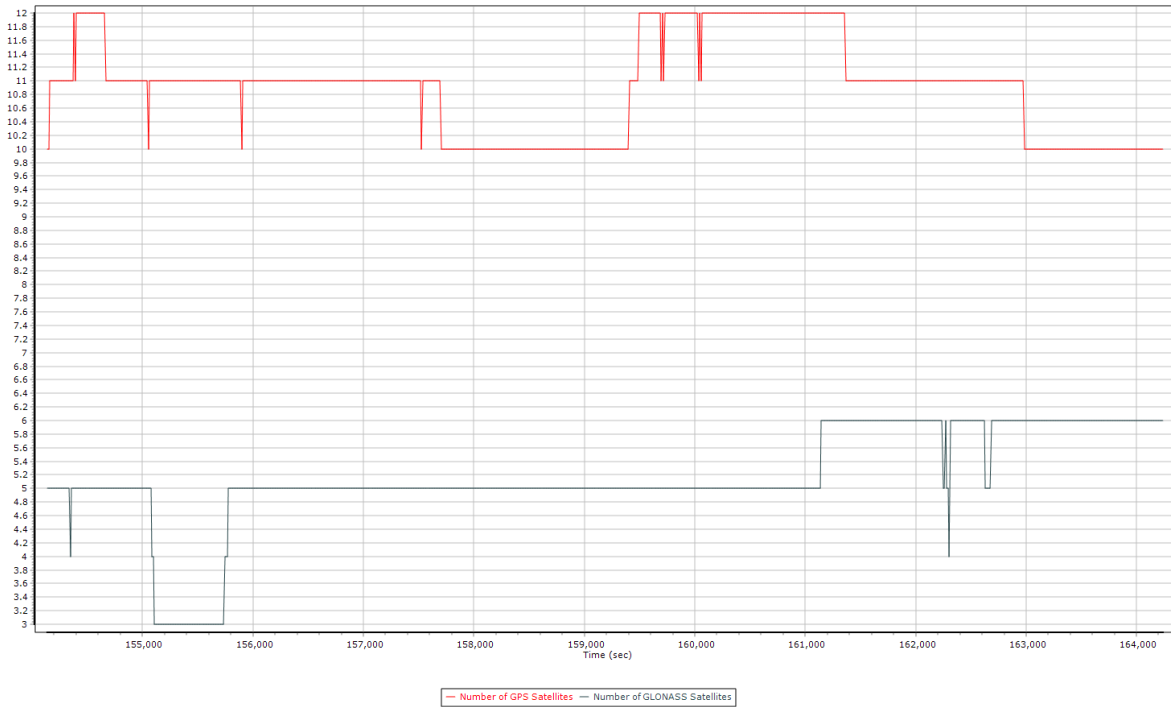
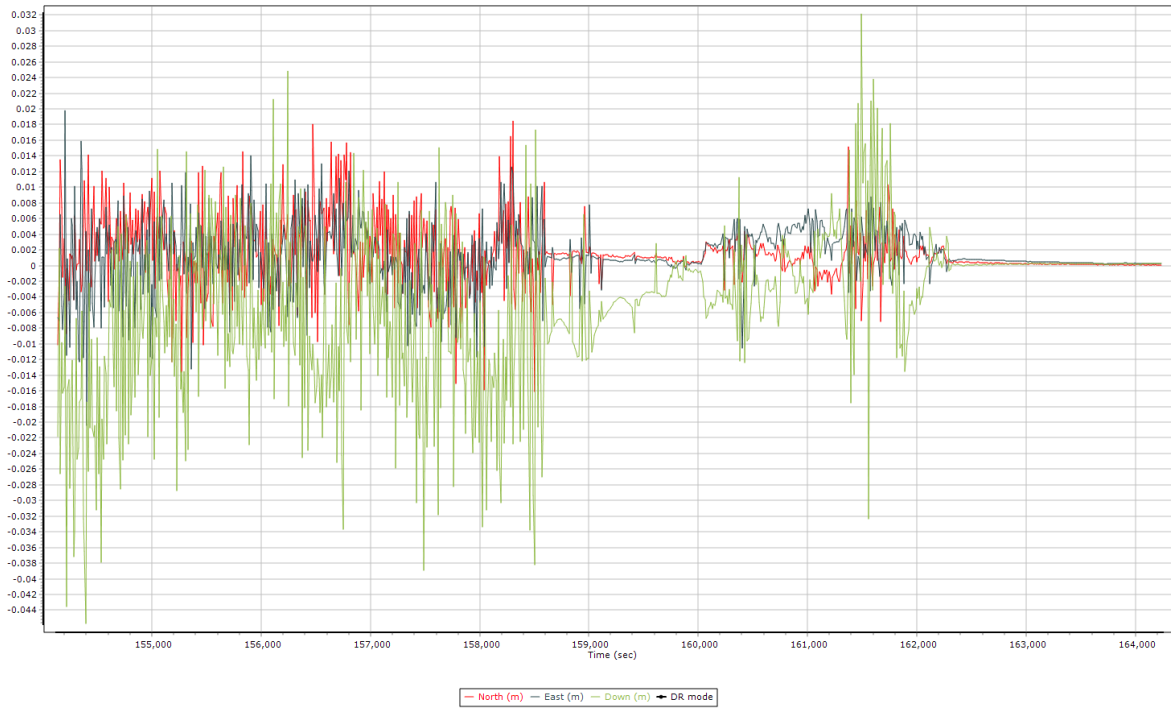
UTC Offset: 18.000

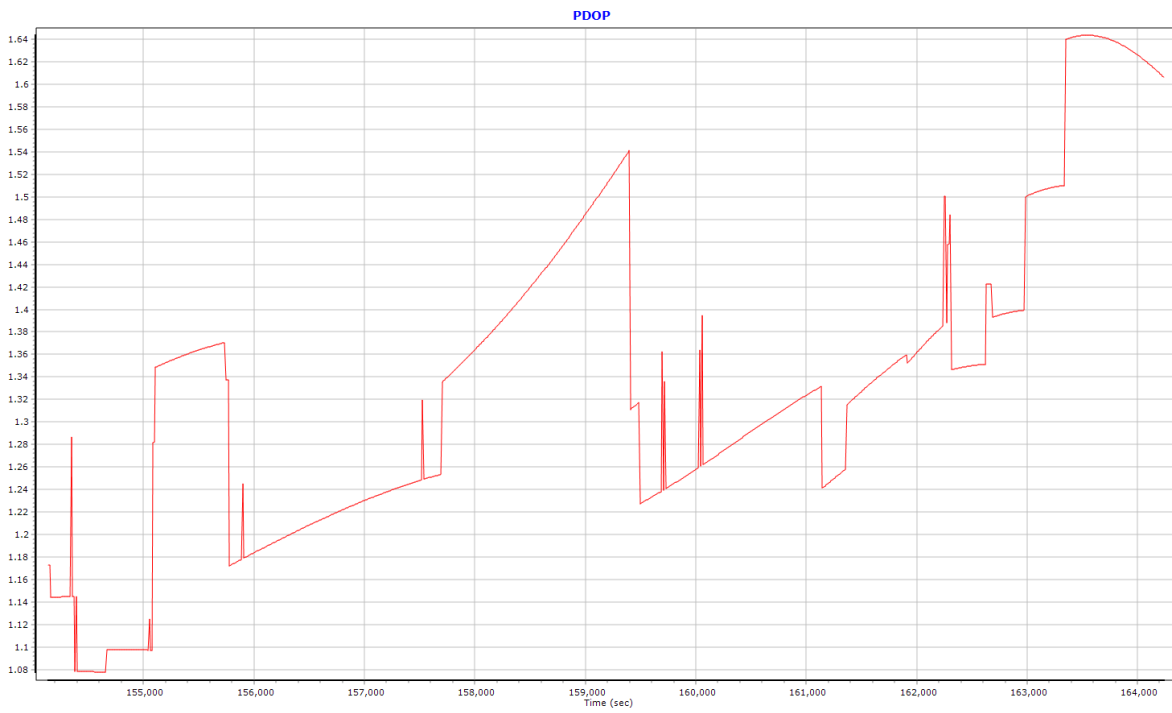
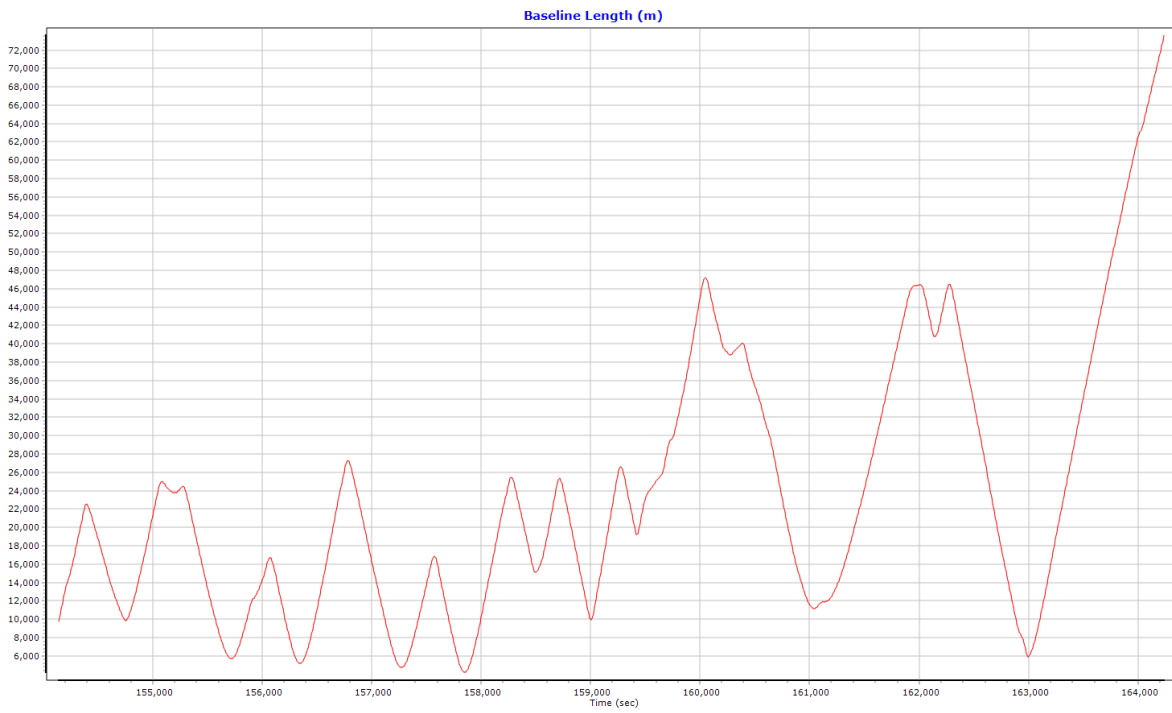
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

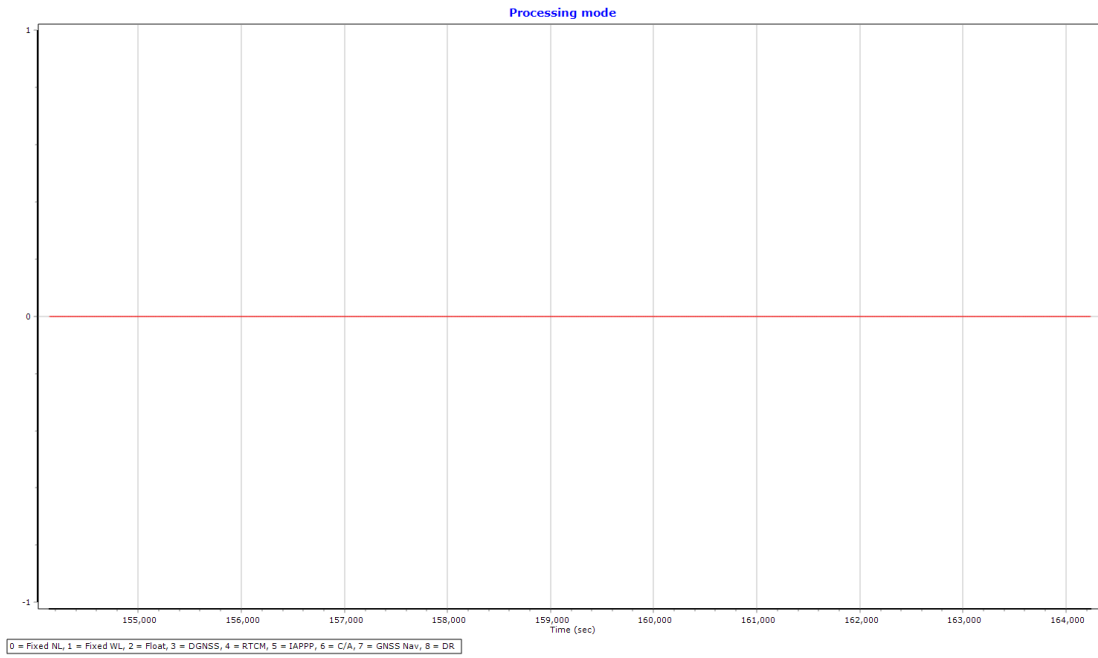
OK Cancel



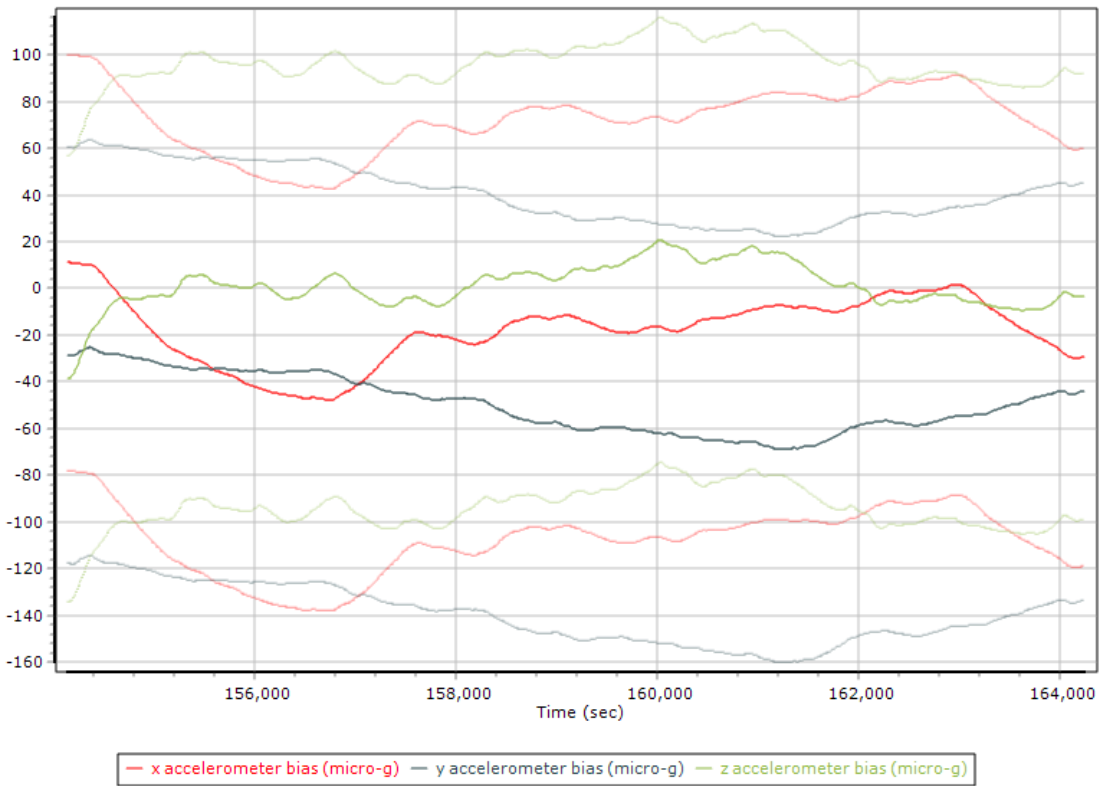


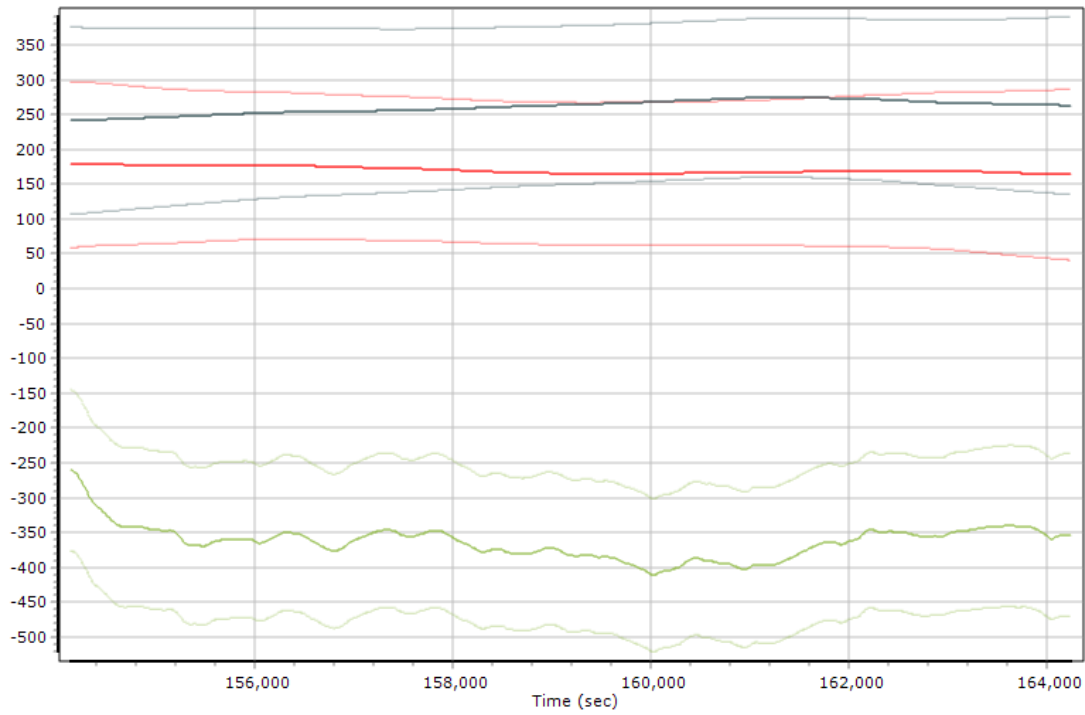




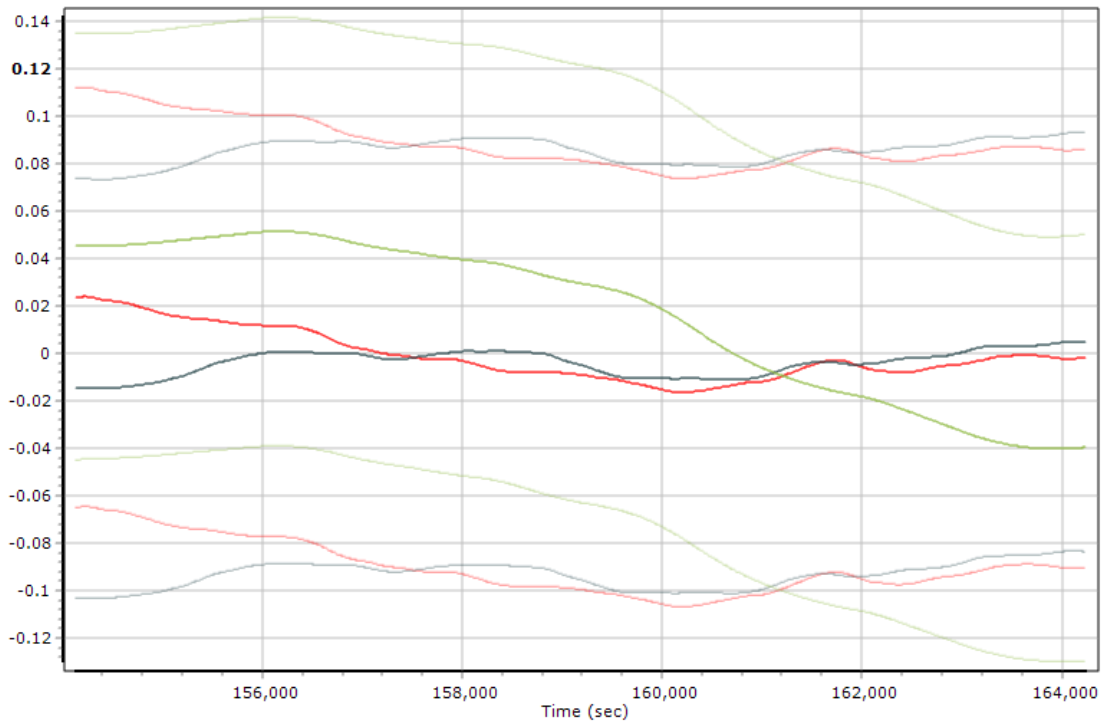


Sensor Errors

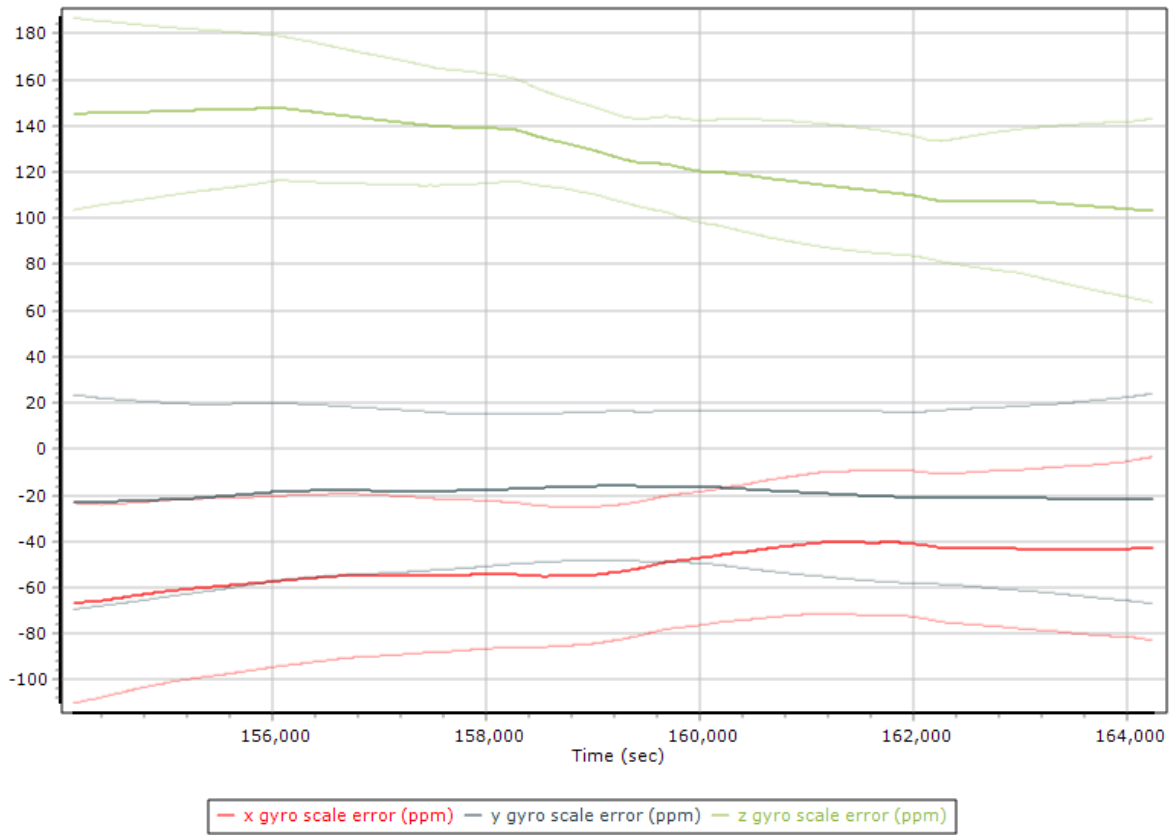




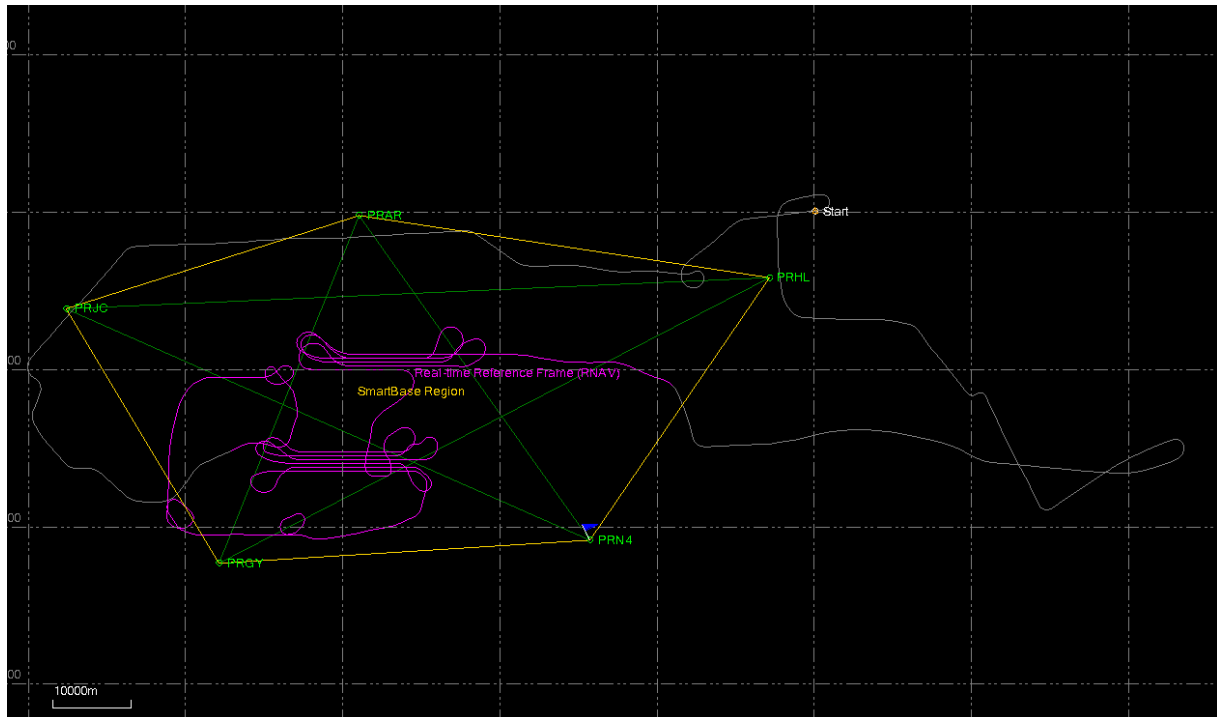
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



RBV18128A



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

Y

Z

Stabilized Mount to IMU Mounting Angles

X

Y

Z

Stabilized Mount to Primary GNSS Lever Arm

X

Y

Z

Aircraft to Stabilized Mount Mounting Angles

X

Y

Z

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

Timing

Start

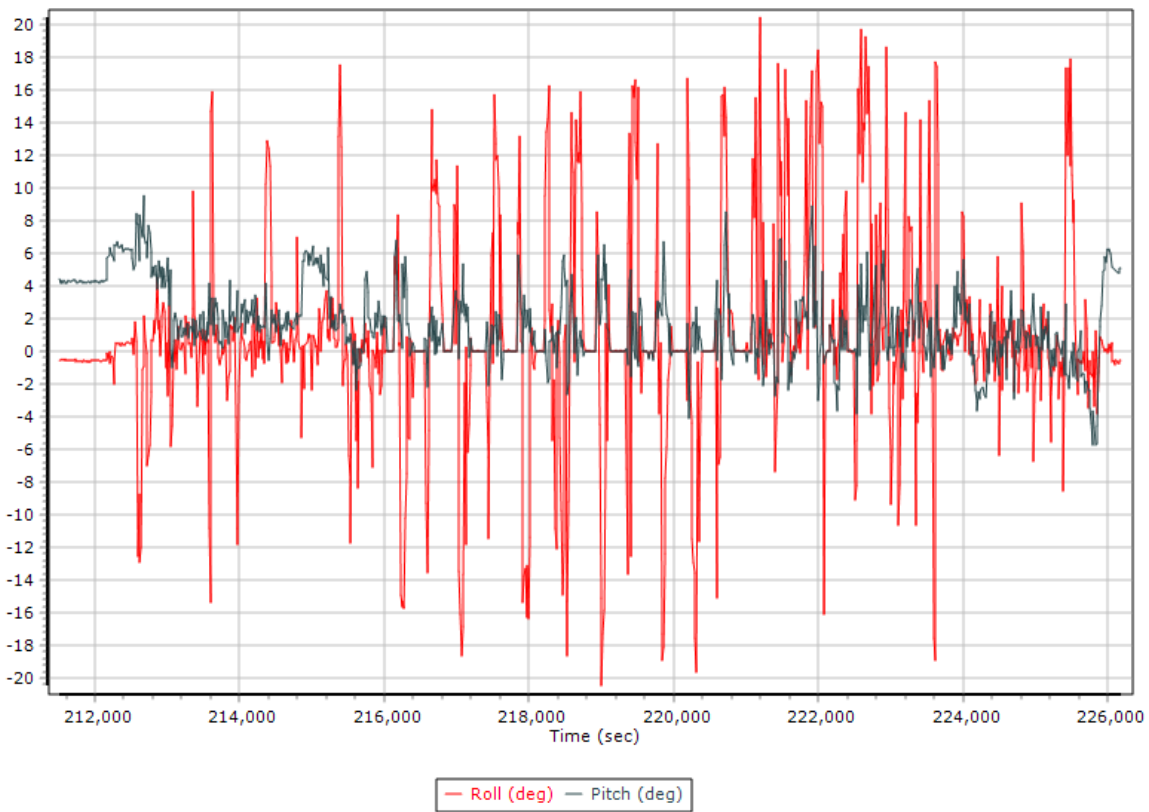
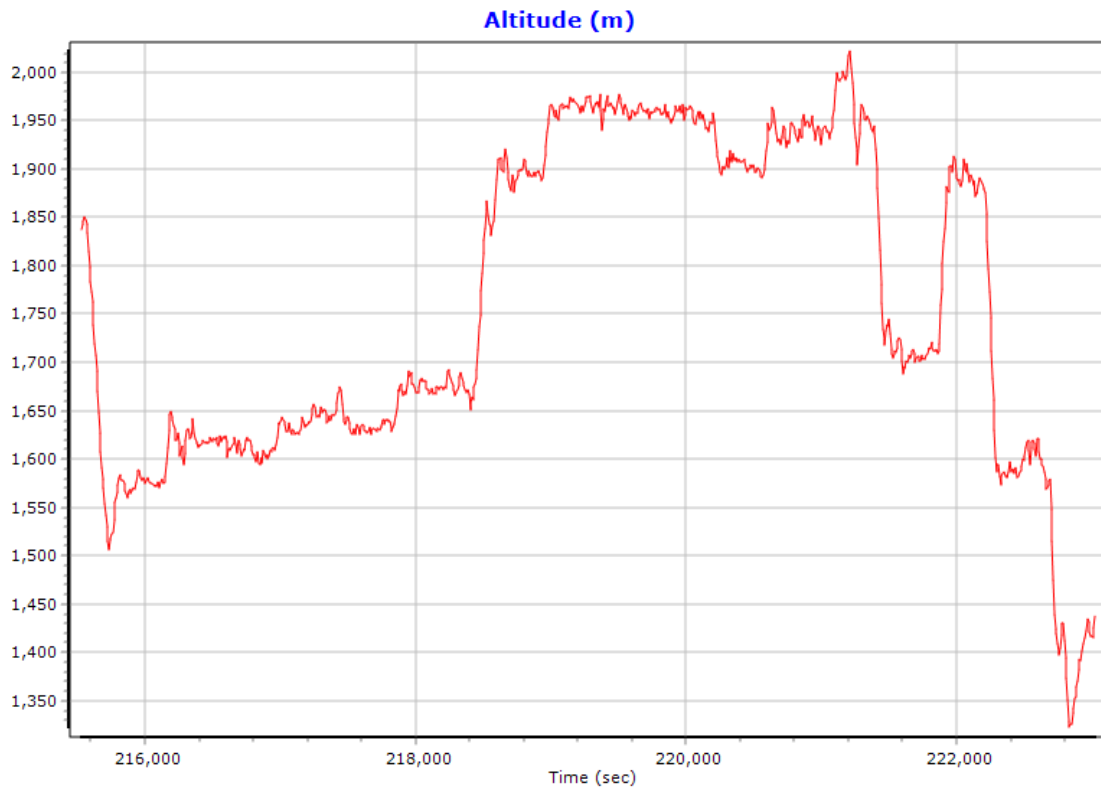
End

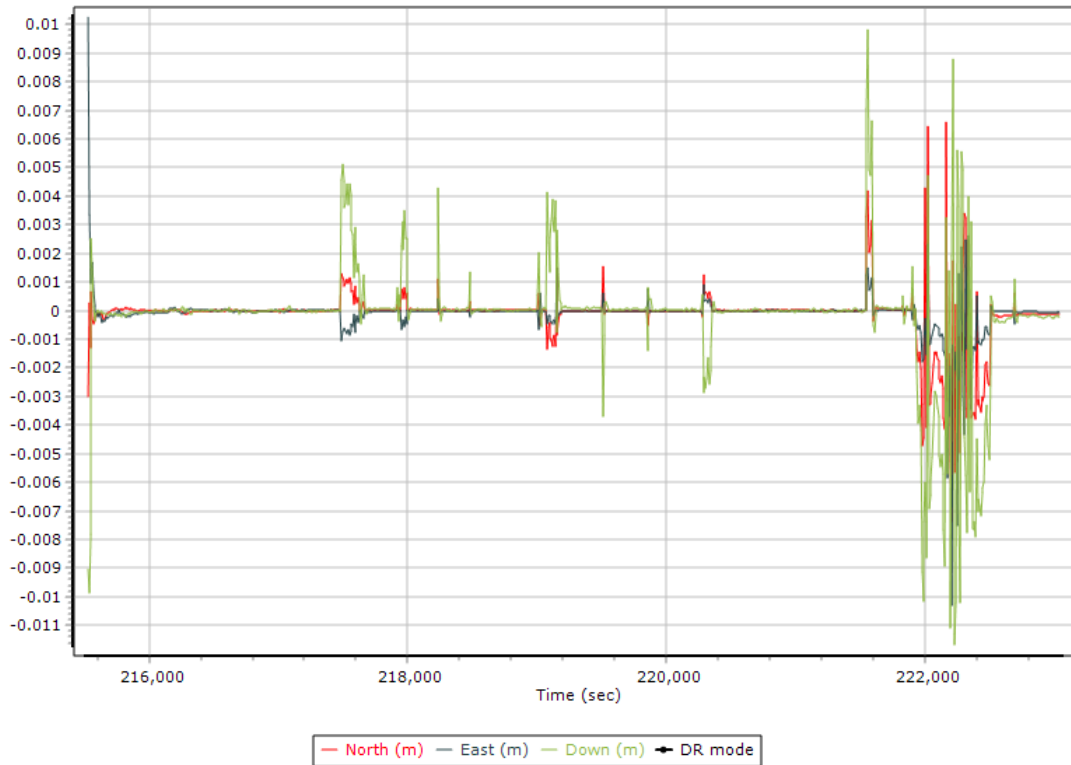
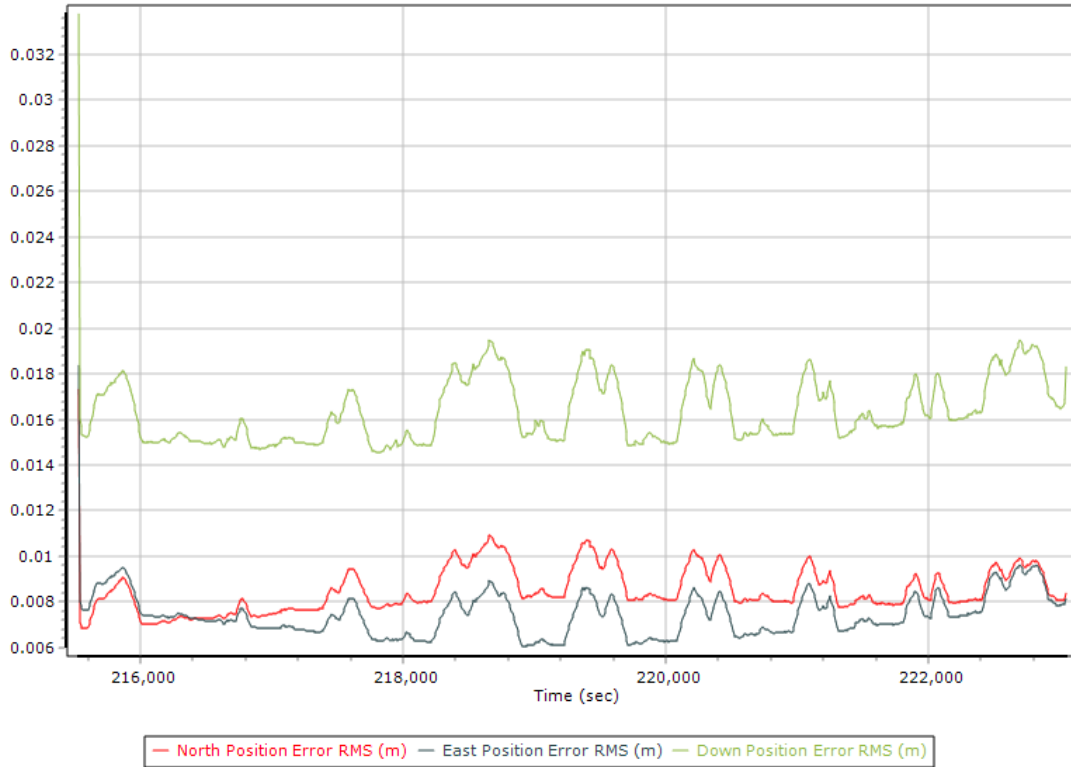
Entire time interval

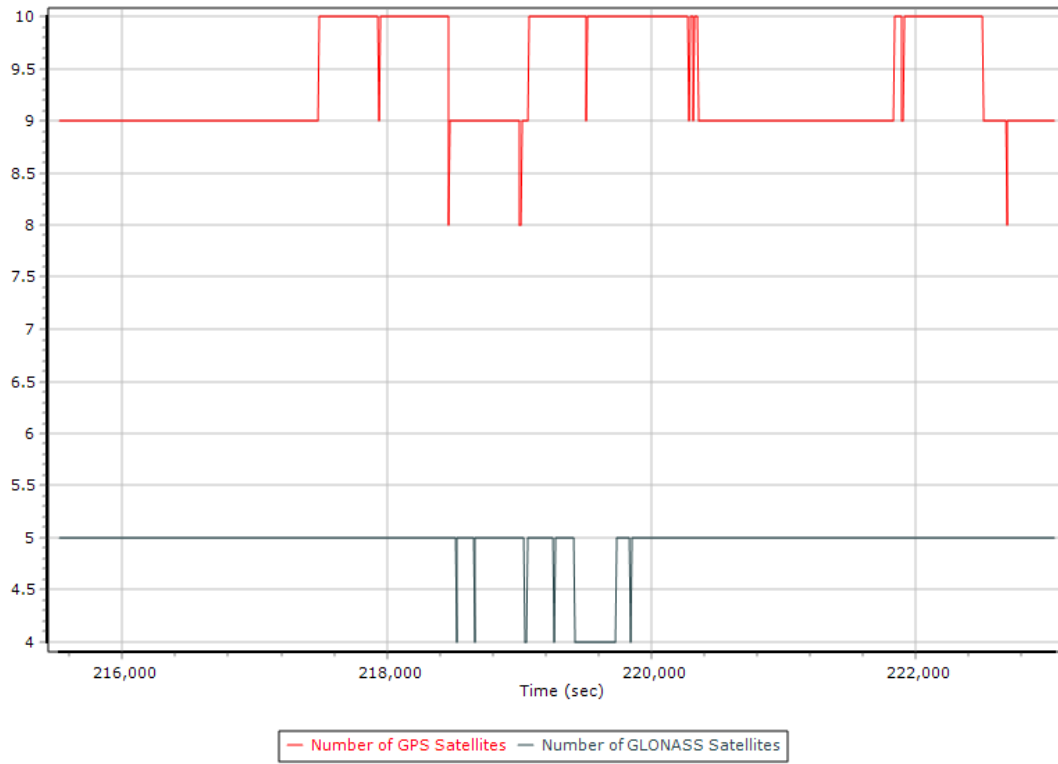
Seconds of start week

UTC Offset

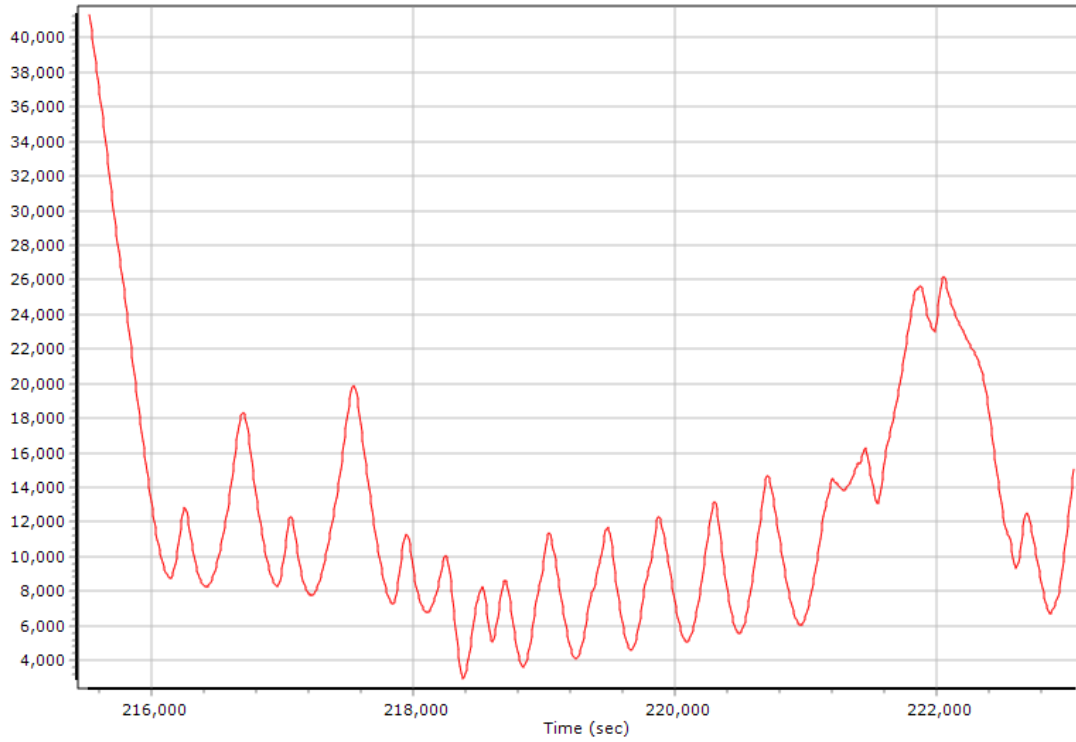
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

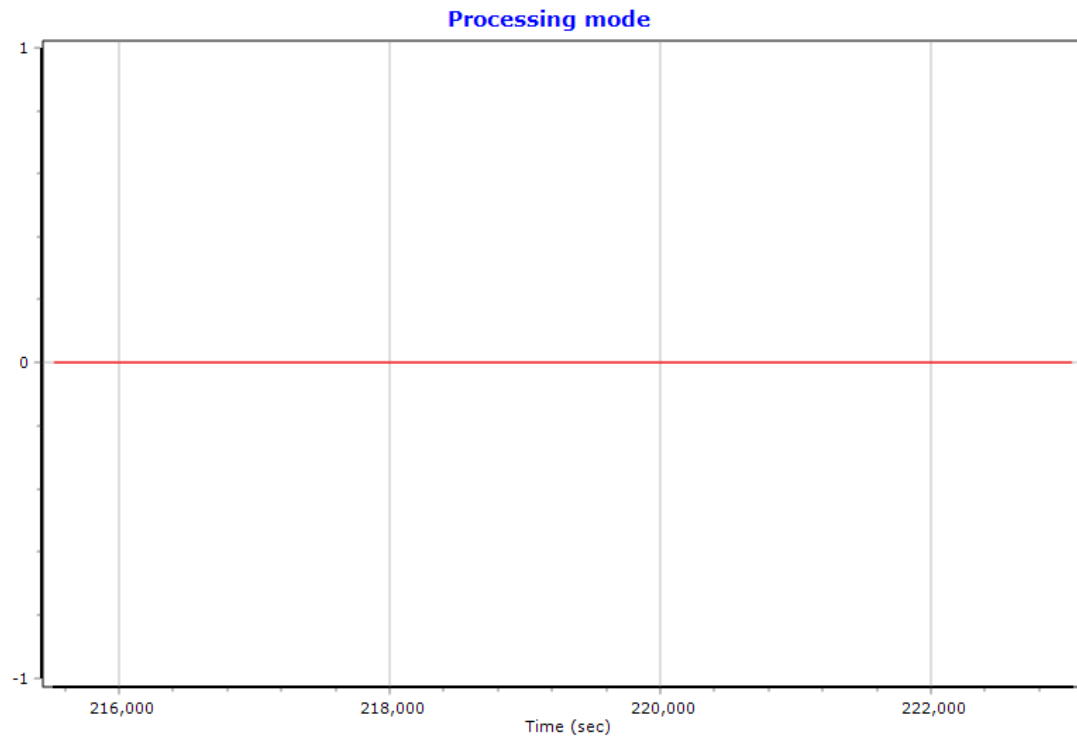
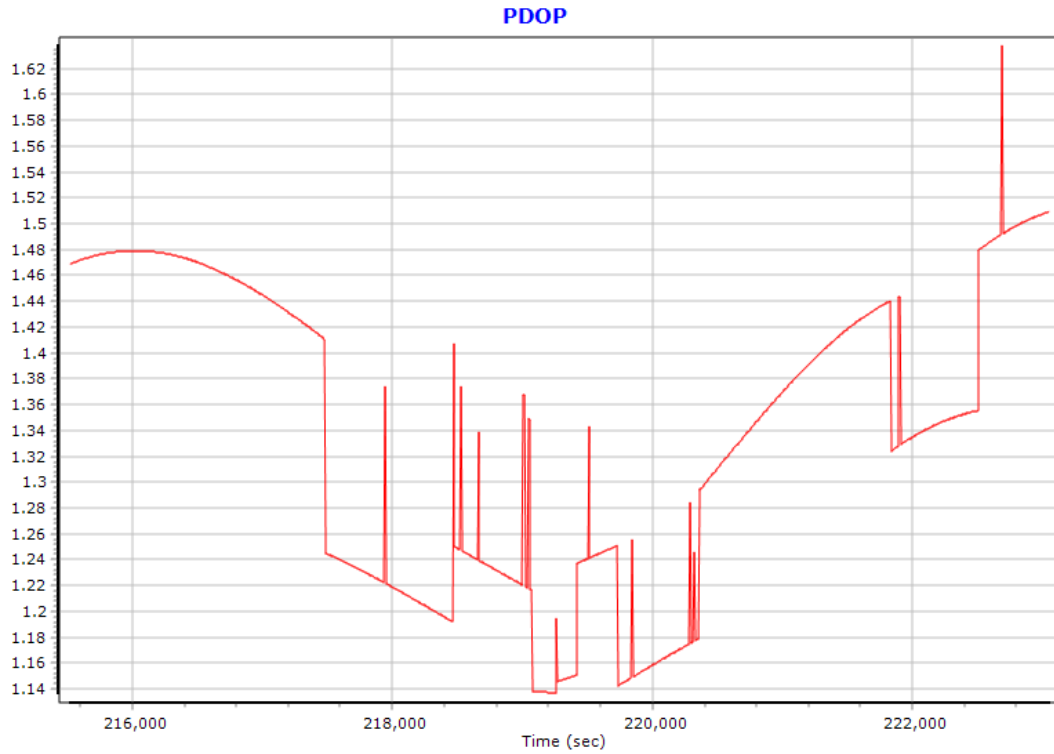






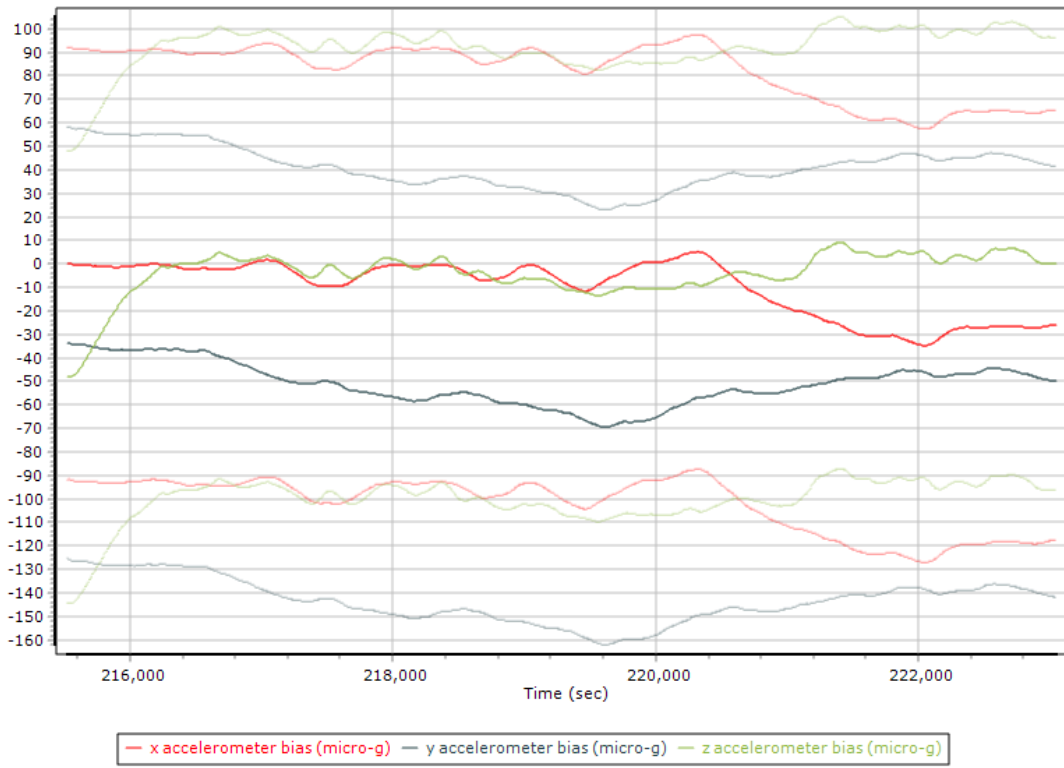
Baseline Length (m)

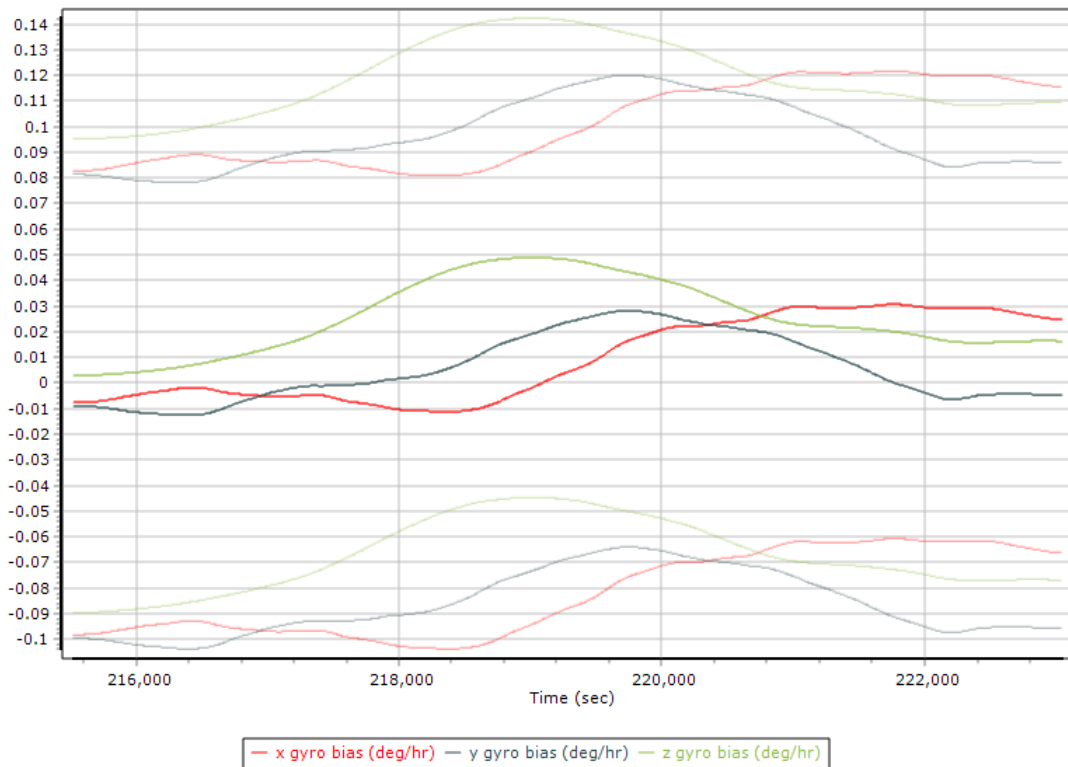
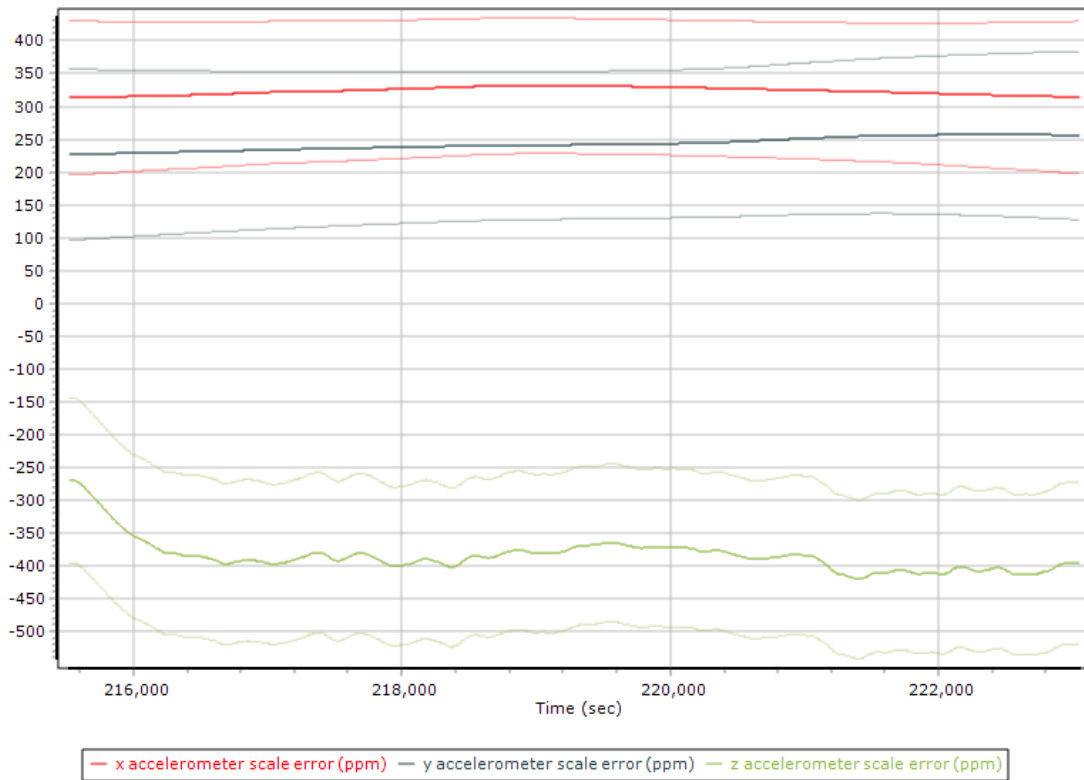


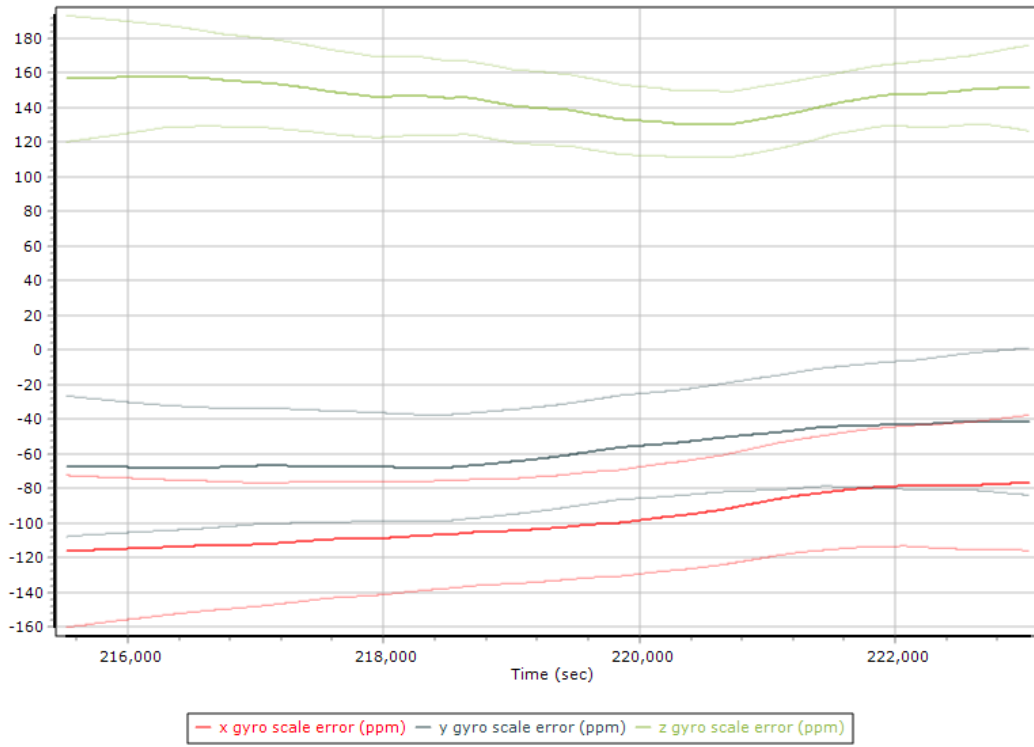


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

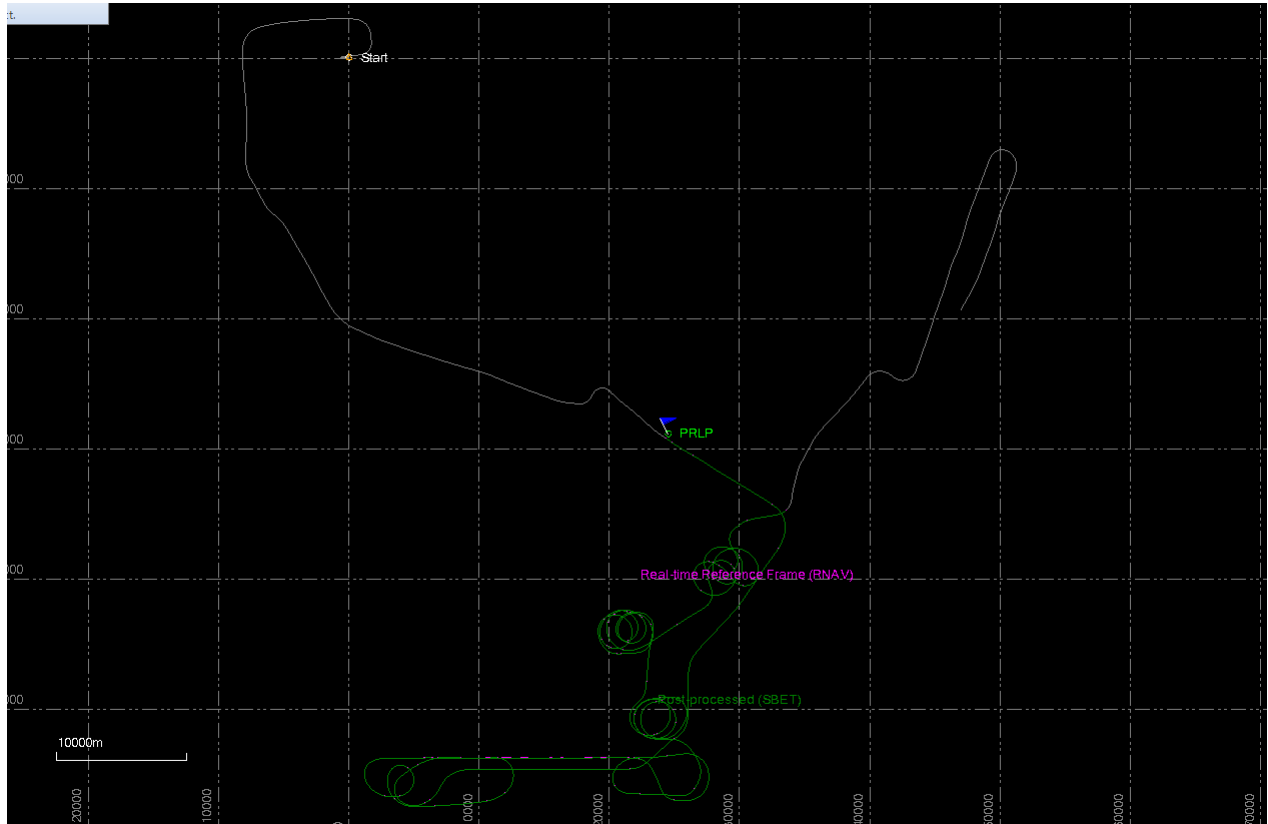
Sensor Errors







RBV18128B



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

Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.037 m	0.007 m	-0.985 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	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

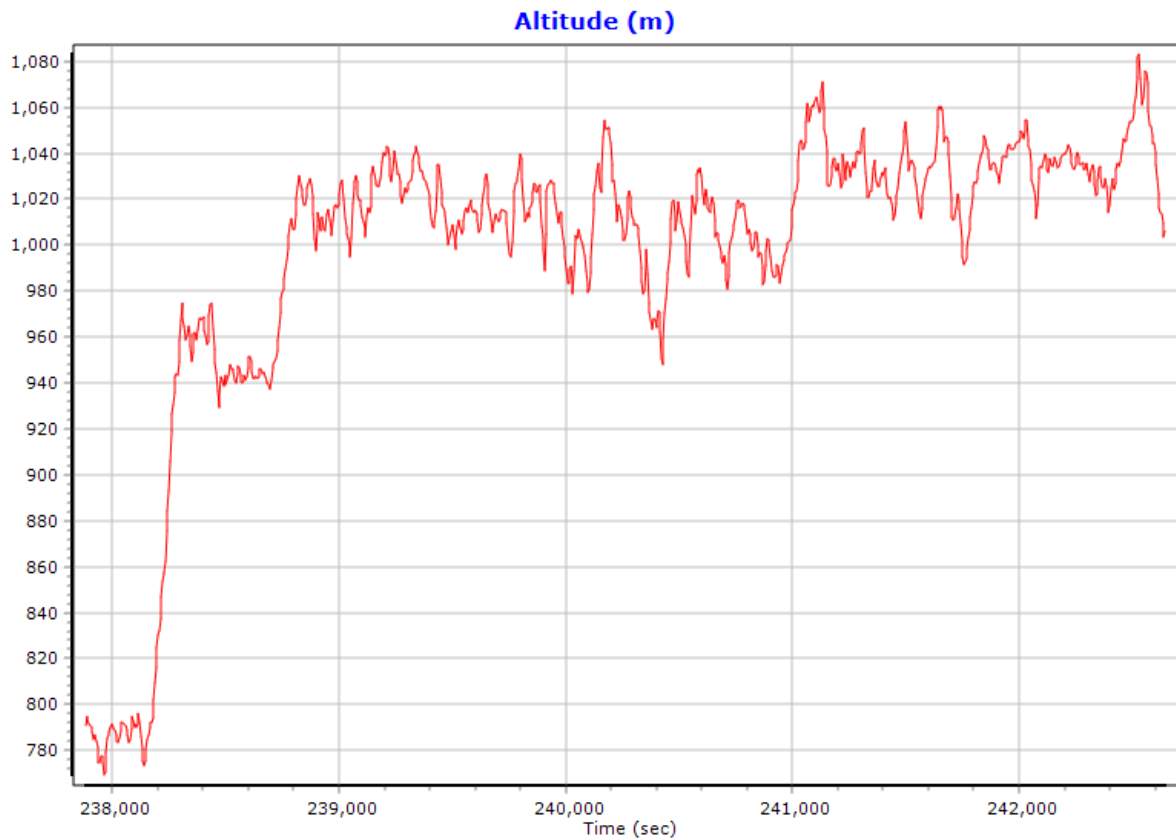
Start: 237882.482
End: 242649.609

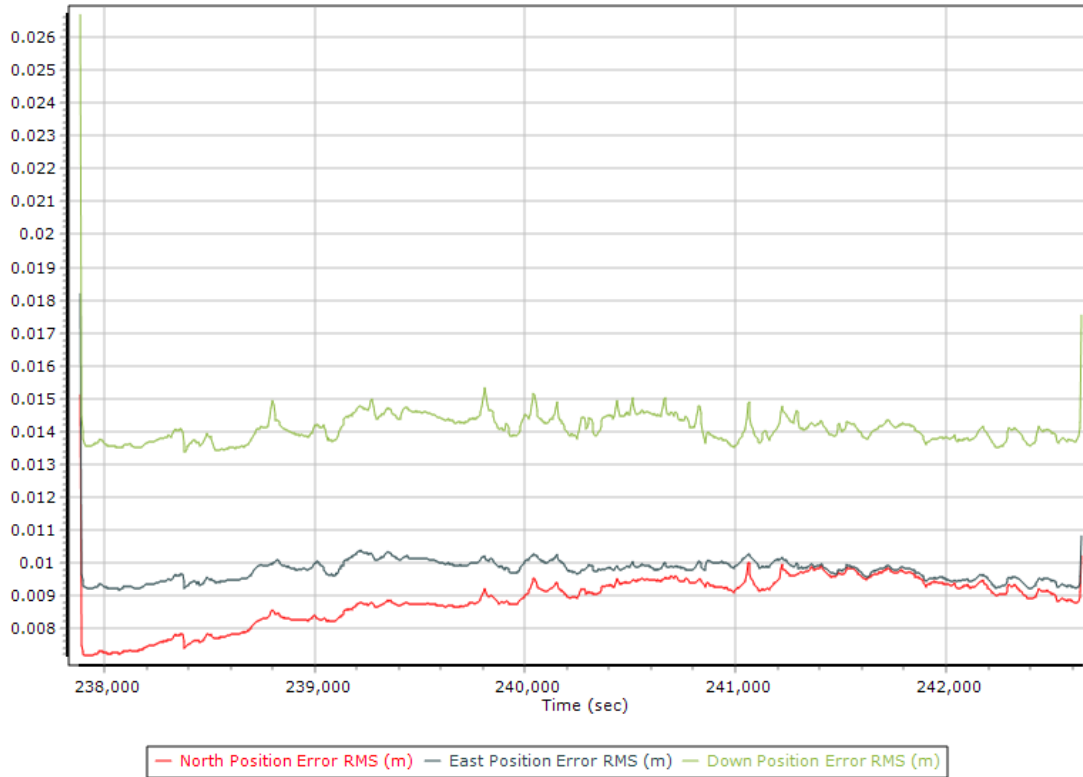
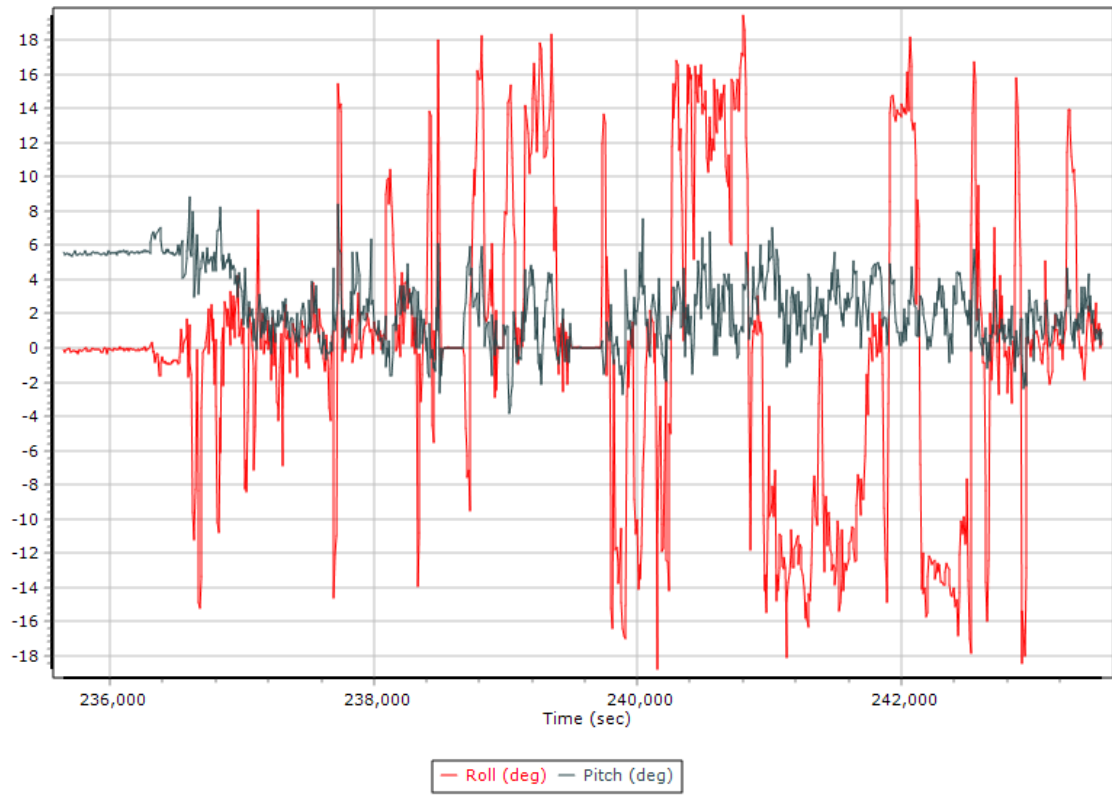
Entire time interval
 Seconds of start week

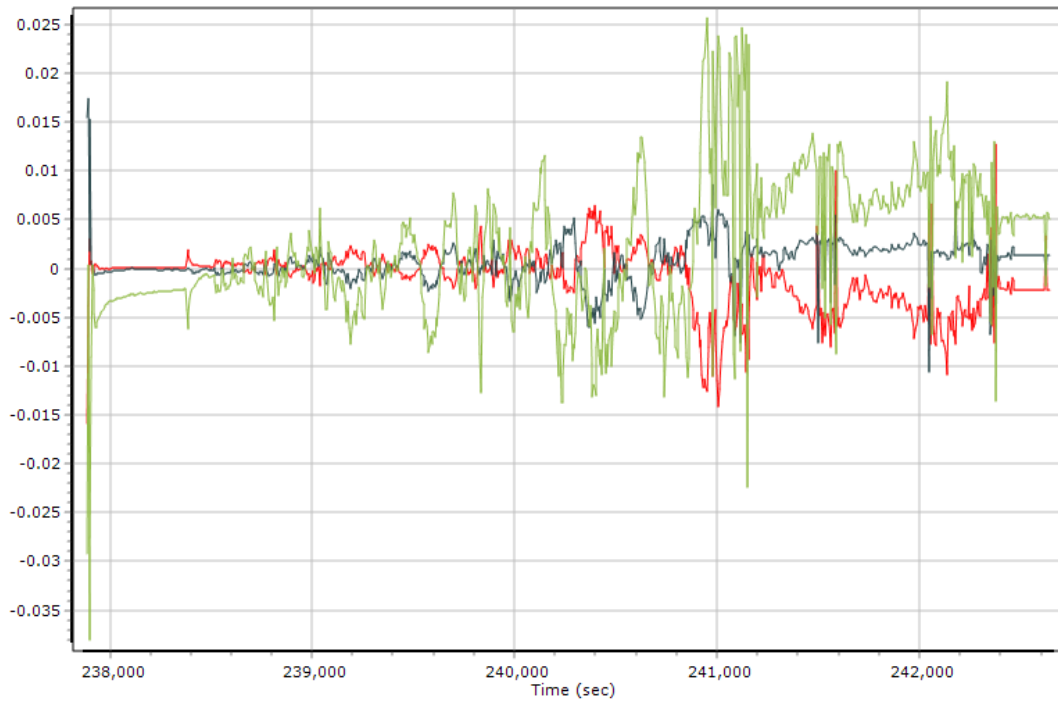
UTC Offset: 18.000

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

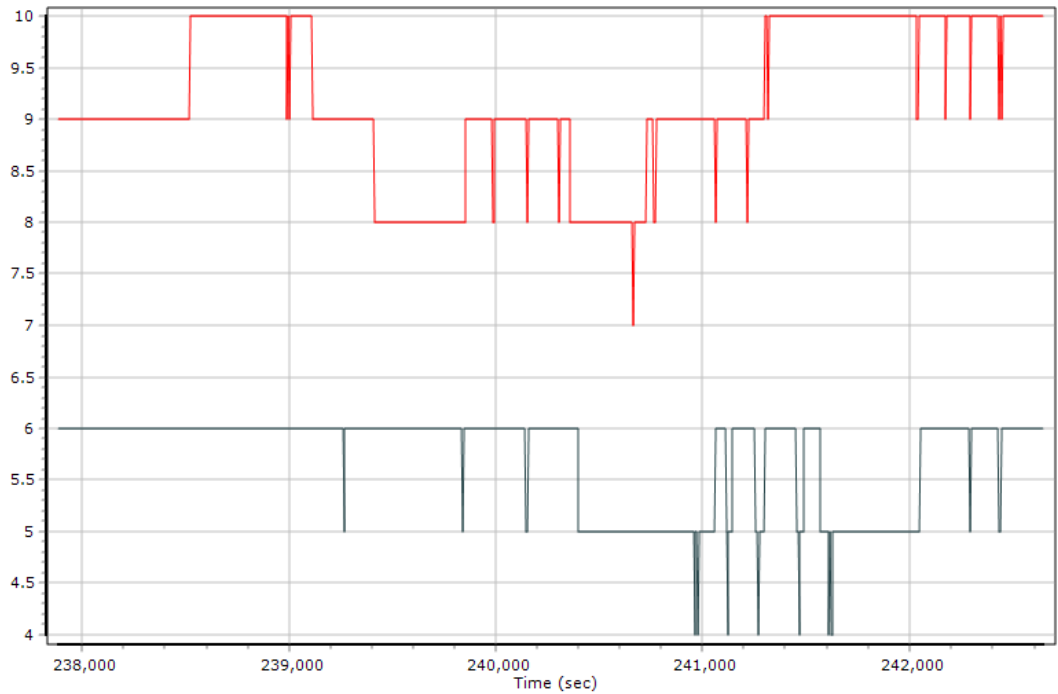
OK Cancel



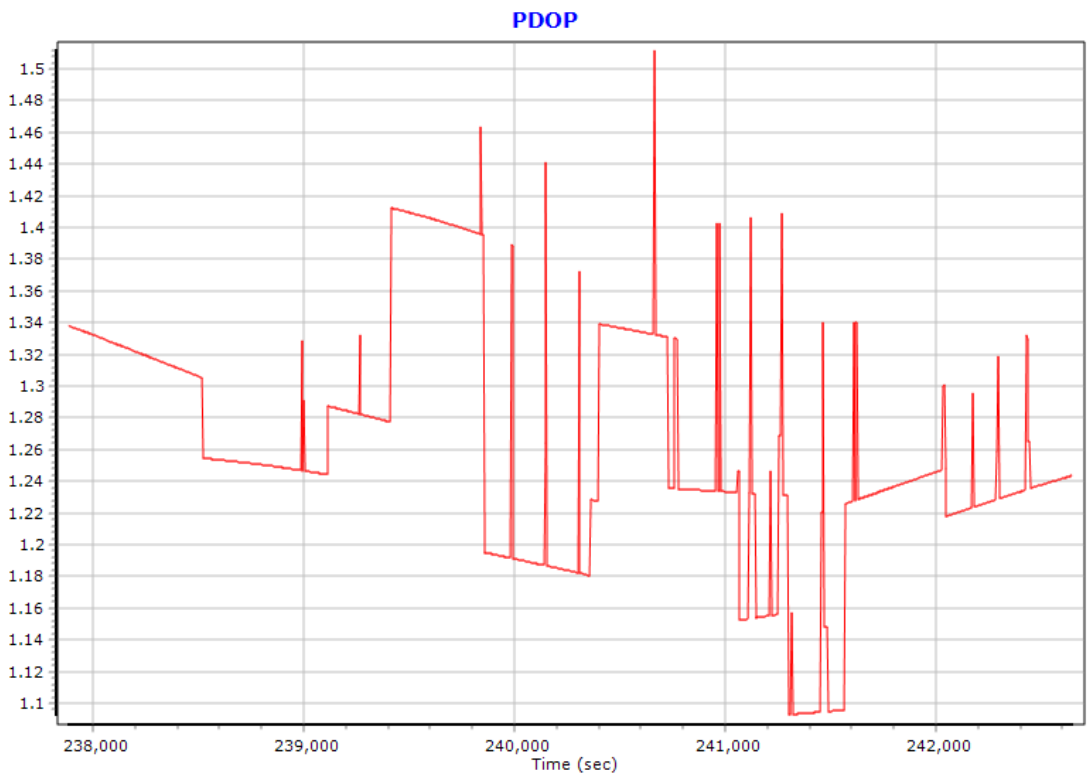
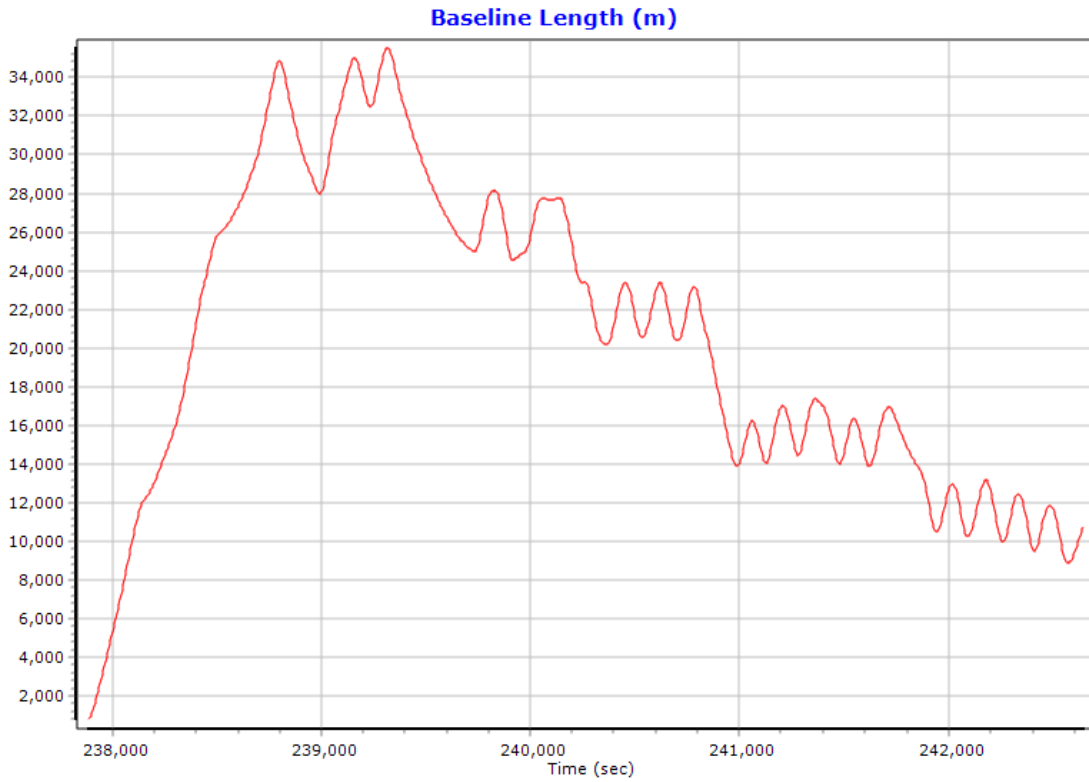


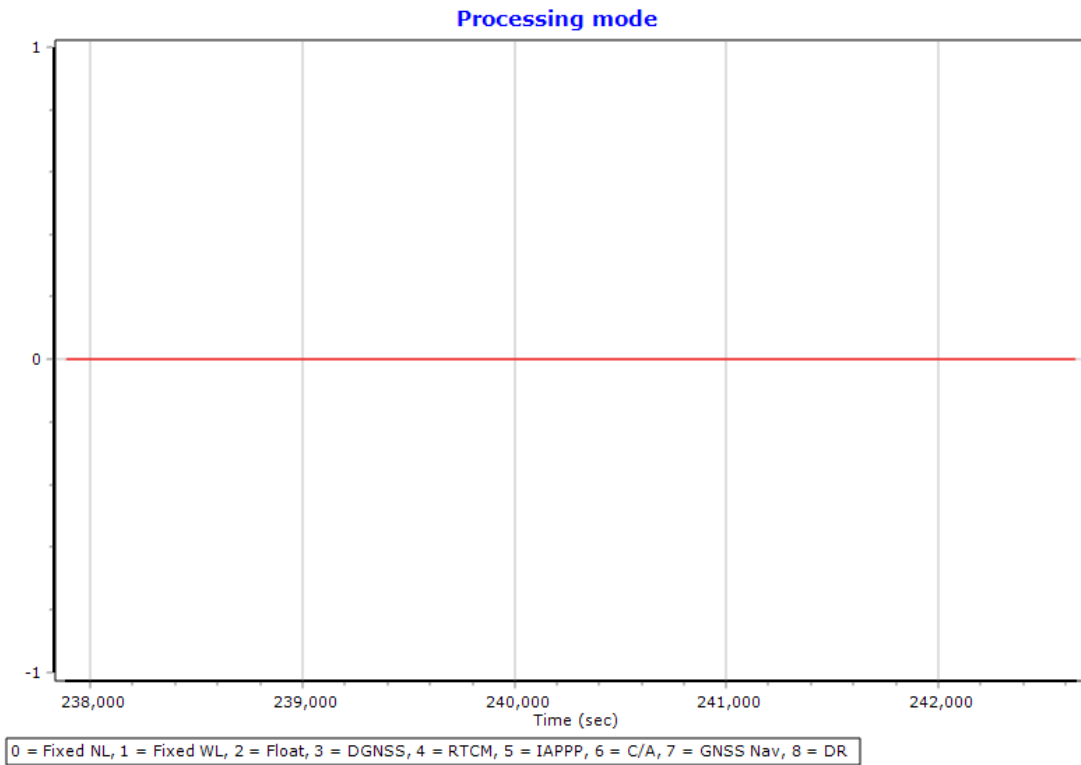


— North (m) — East (m) — Down (m) — DR mode

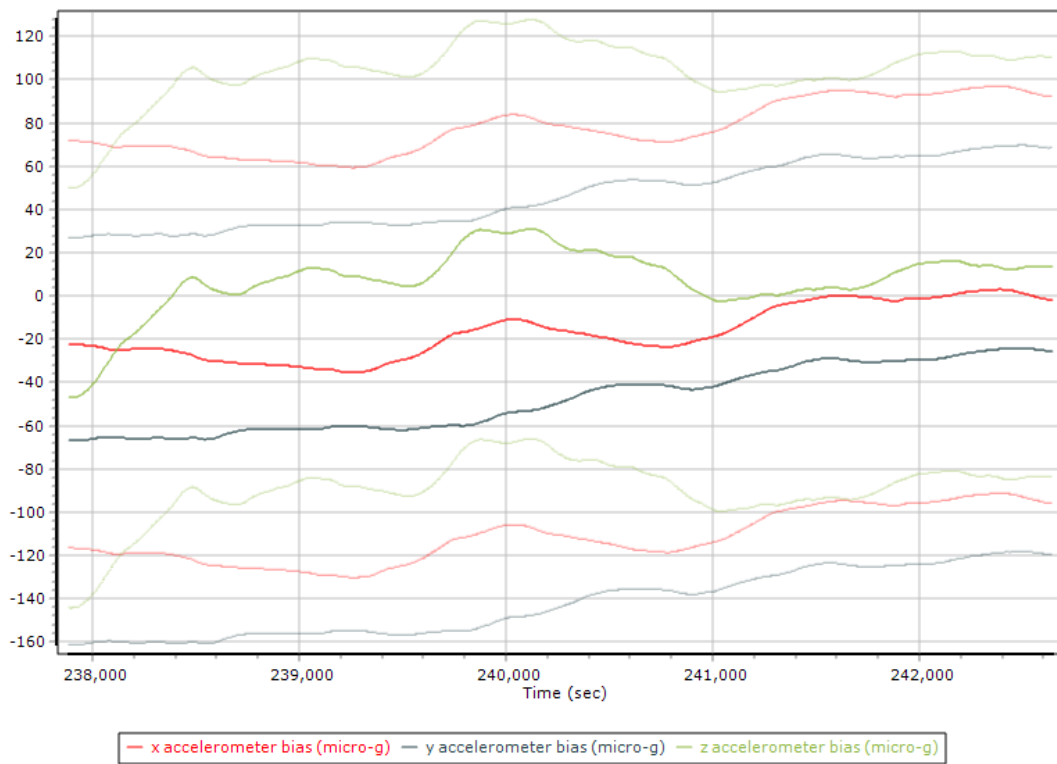


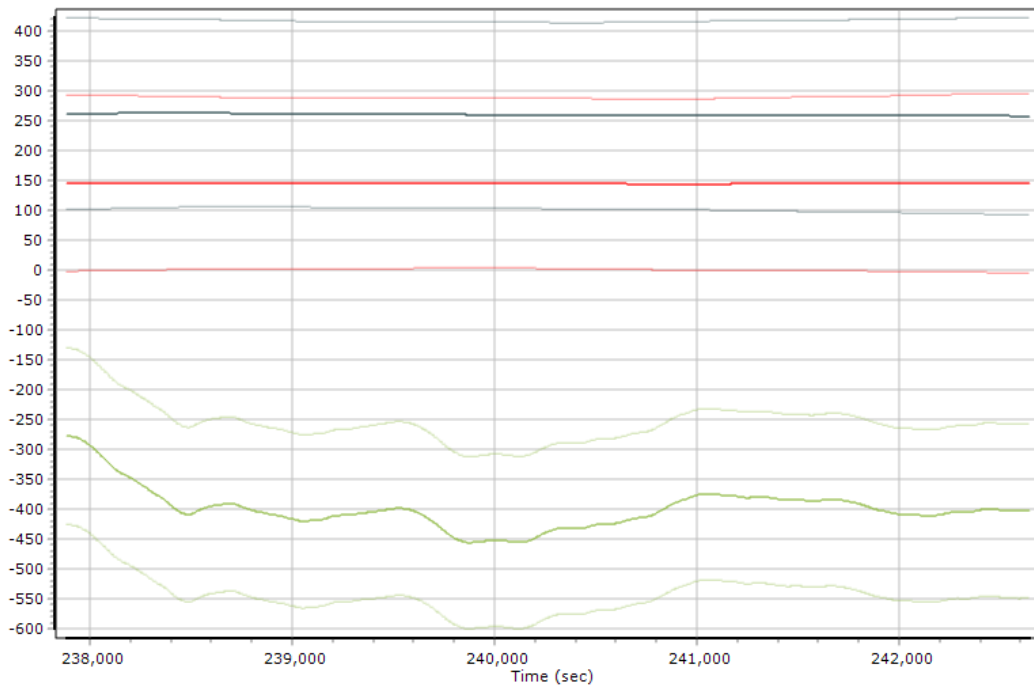
— Number of GPS Satellites — Number of GLONASS Satellites



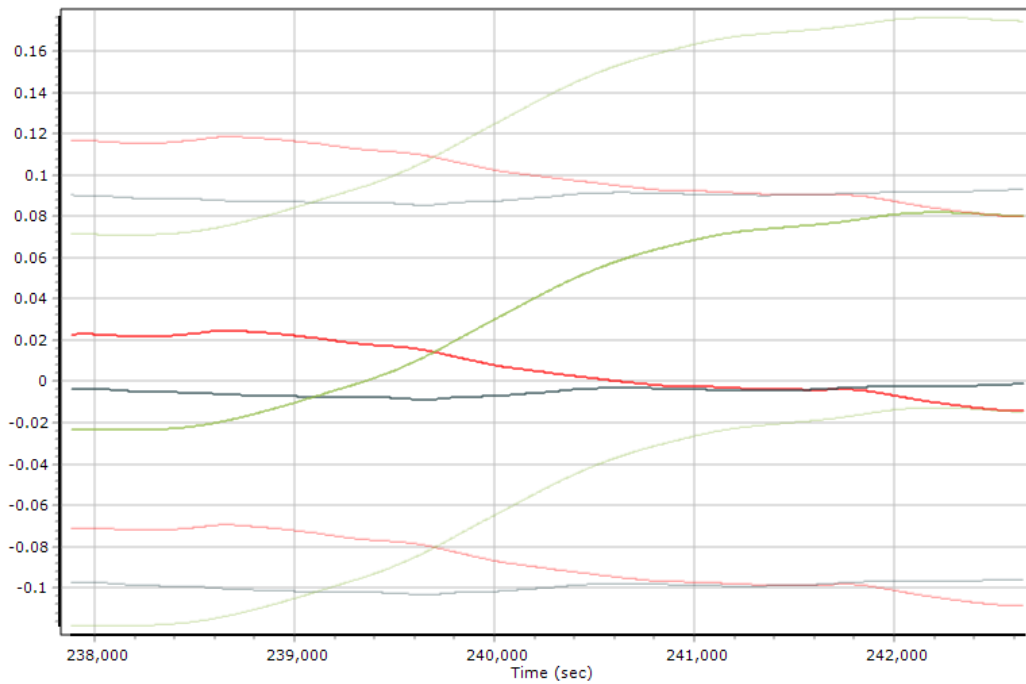


Sensor Errors

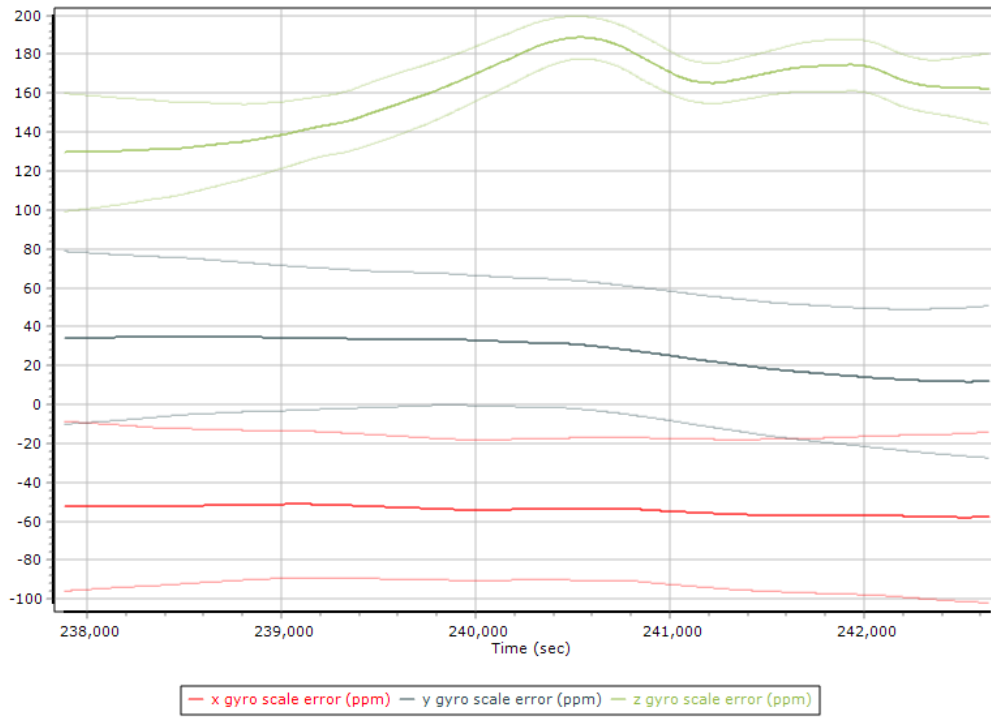




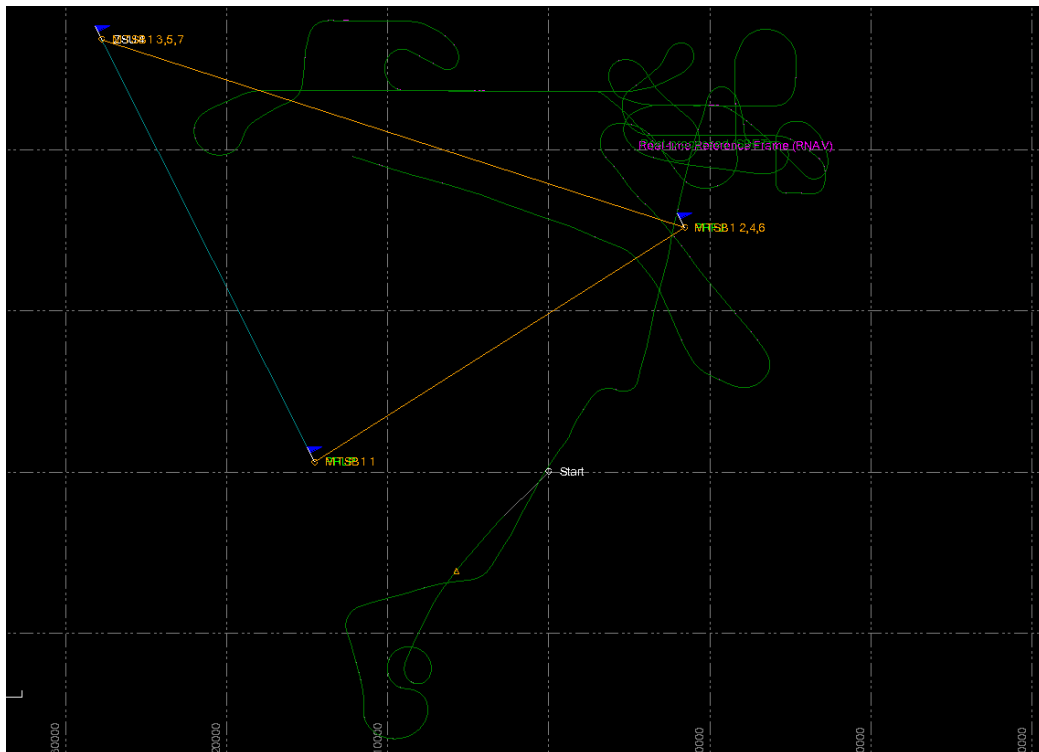
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

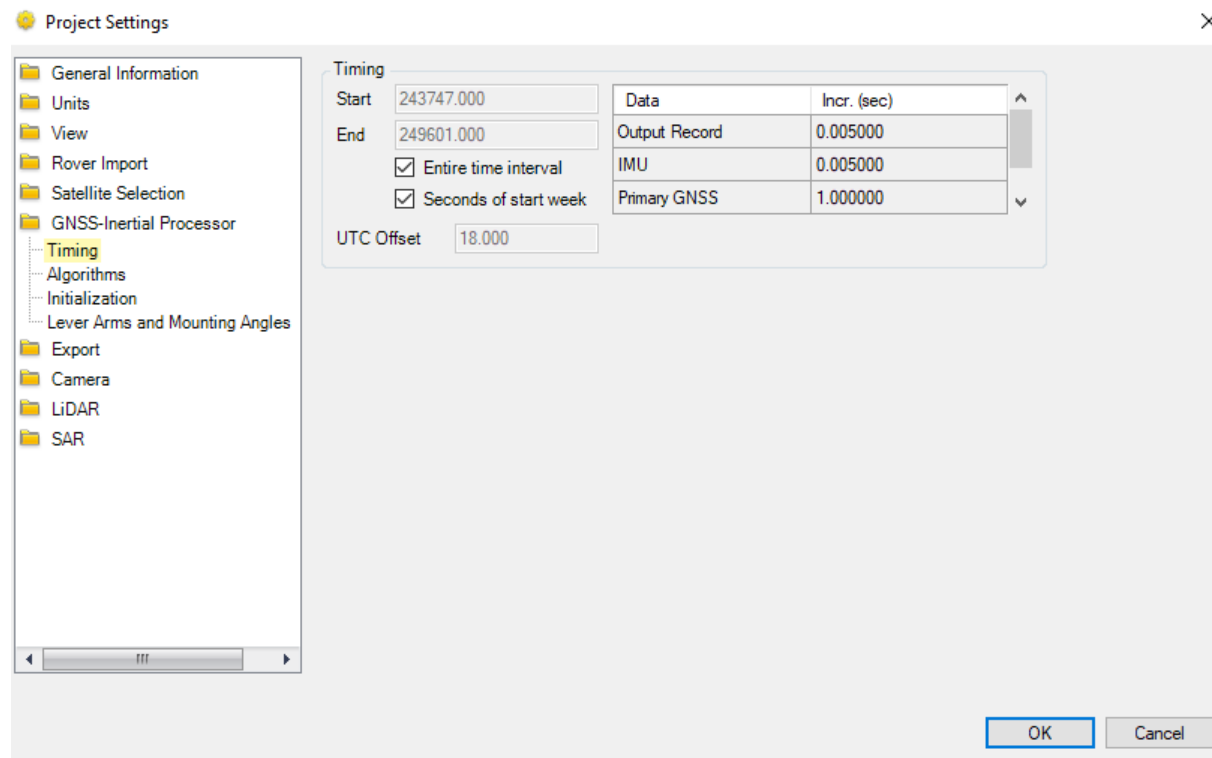
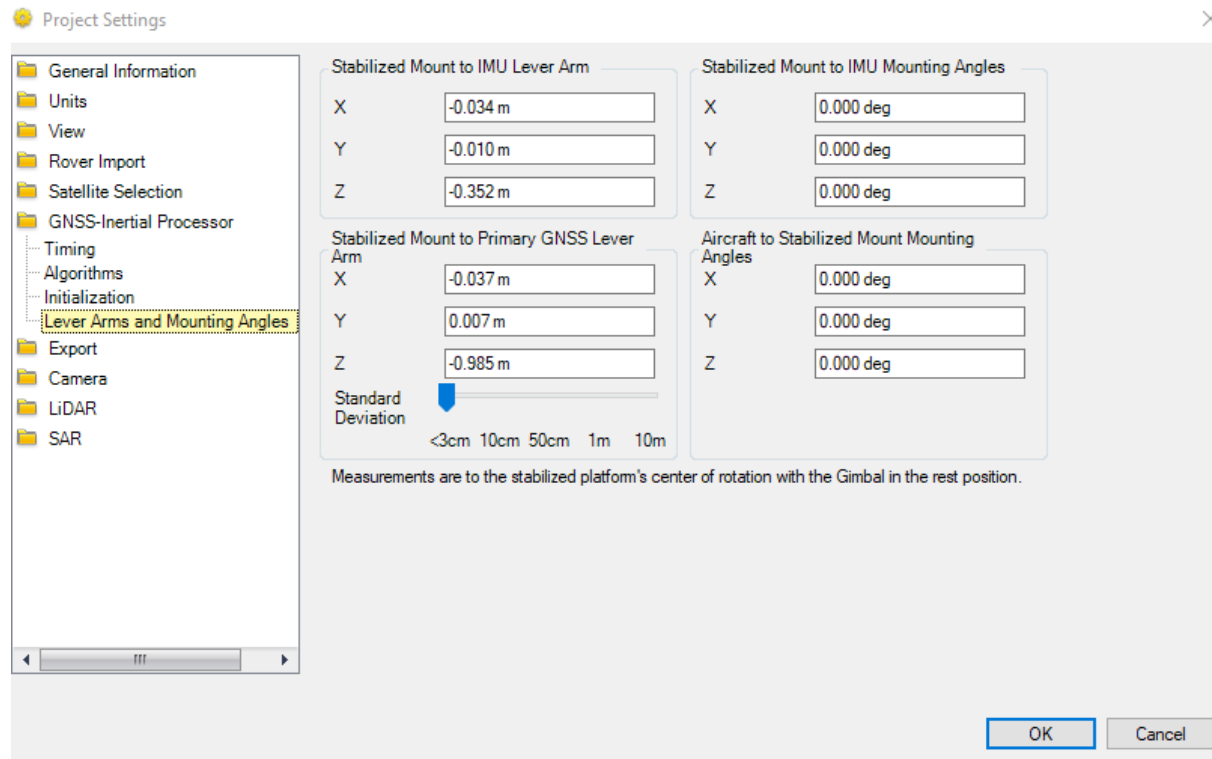


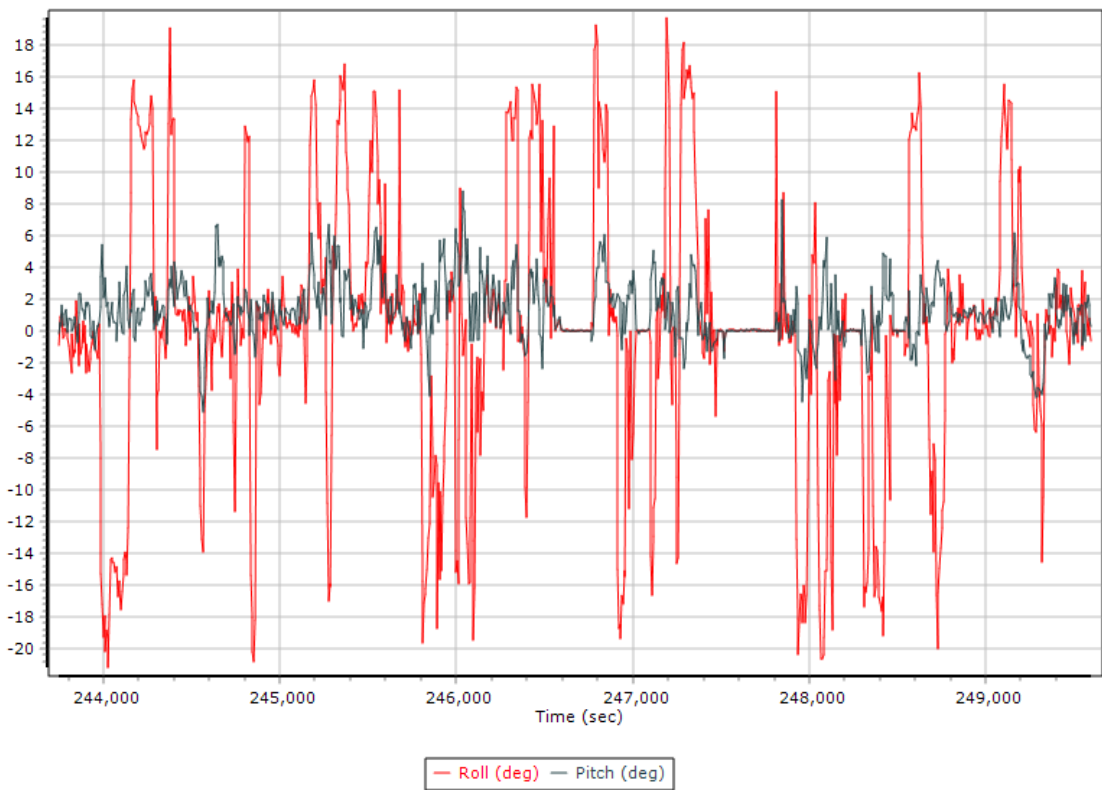
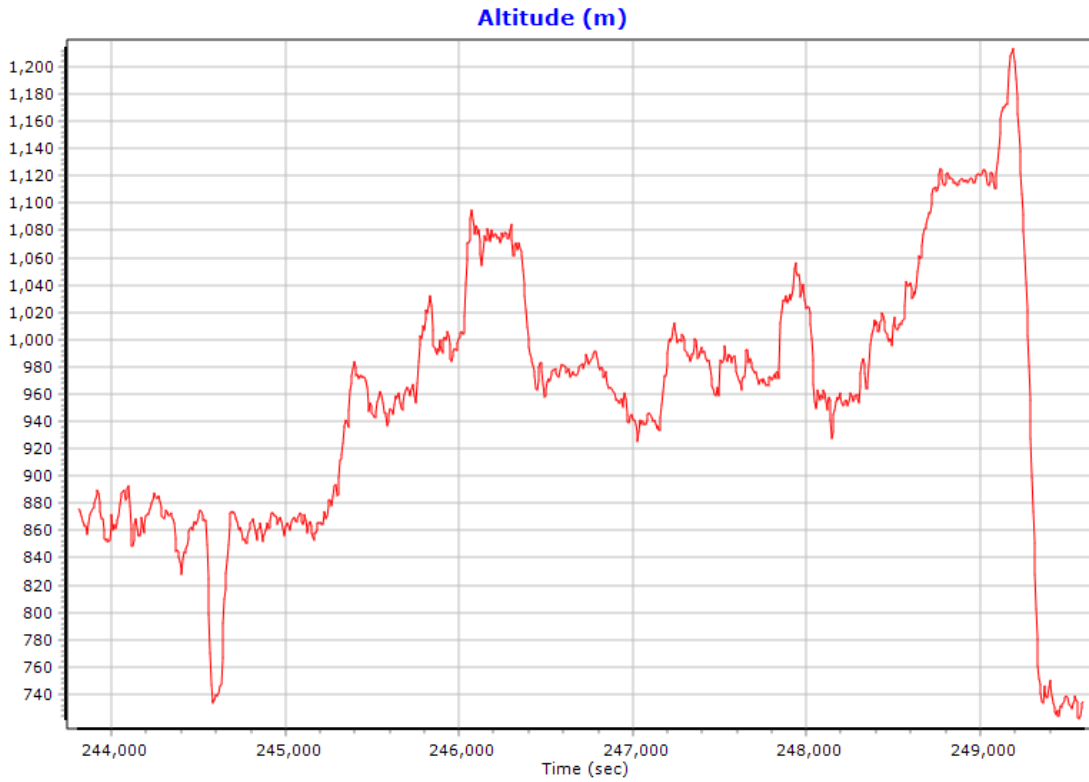
— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

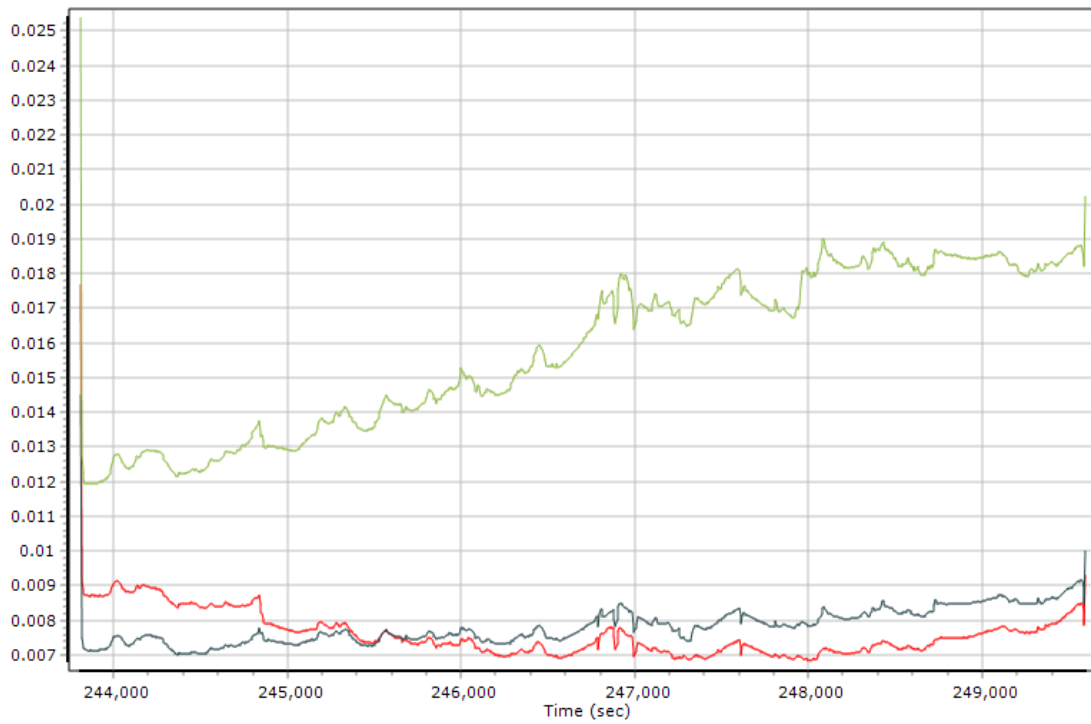


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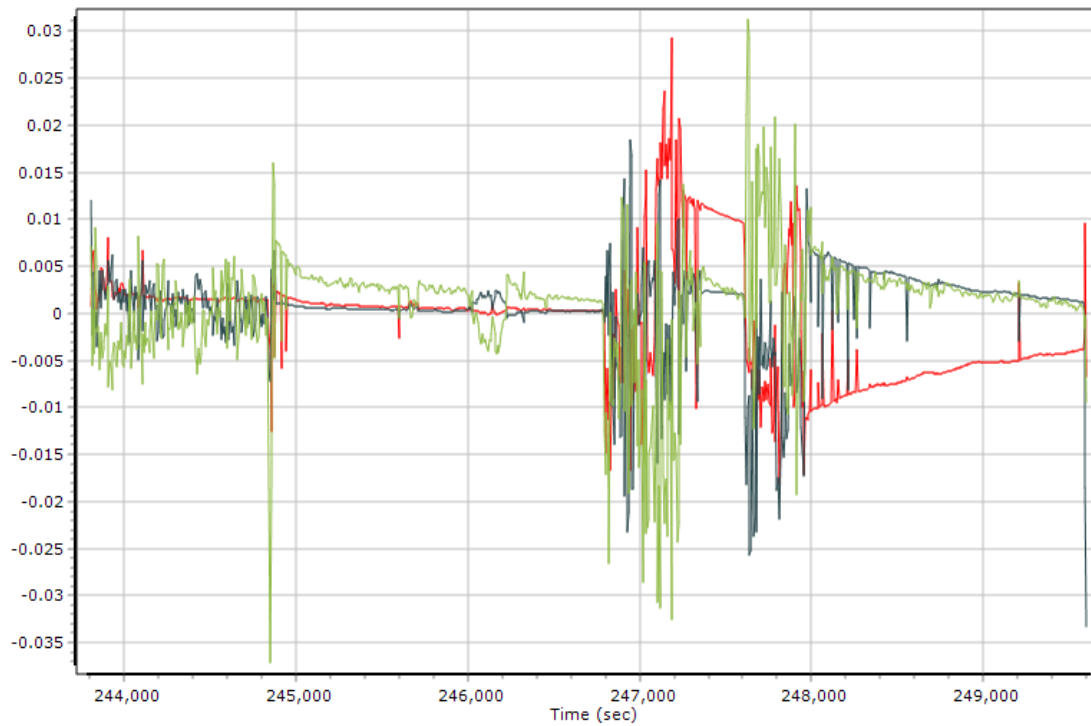




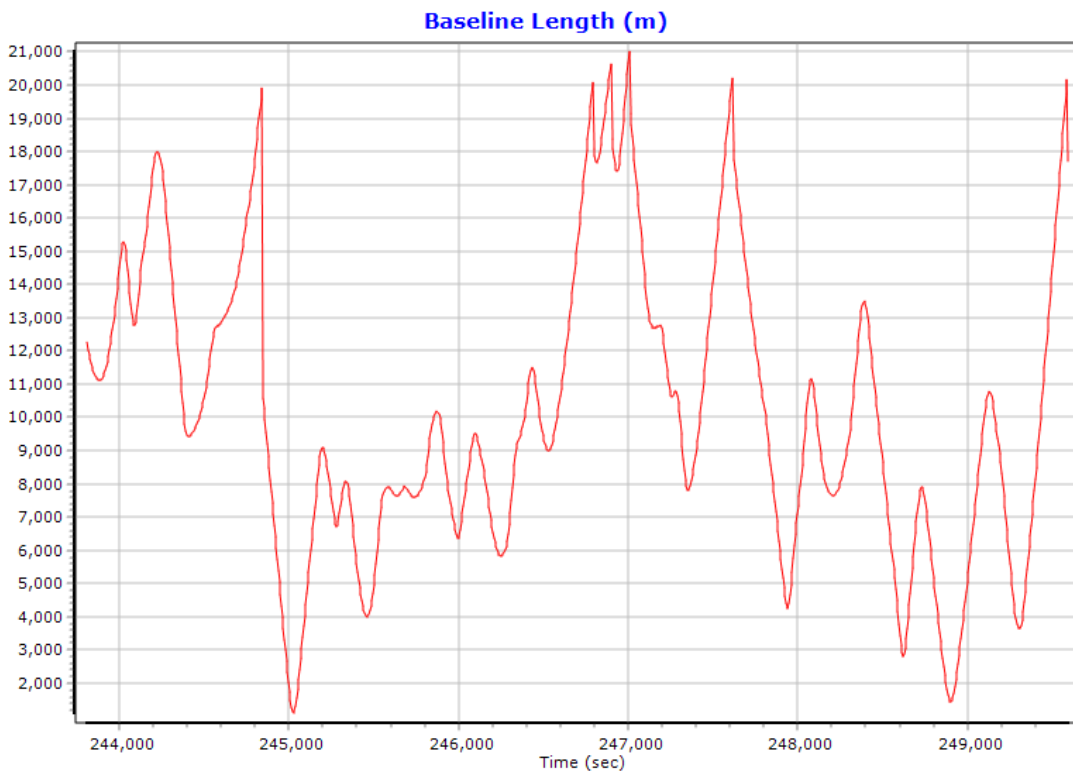
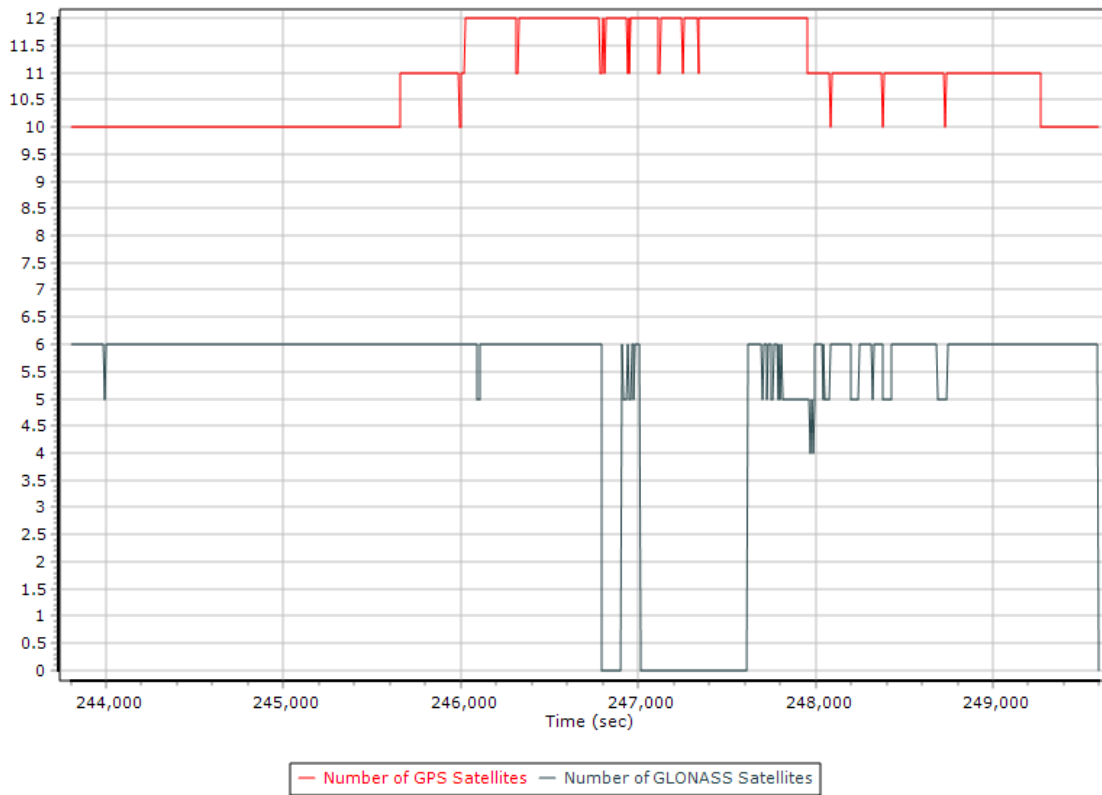




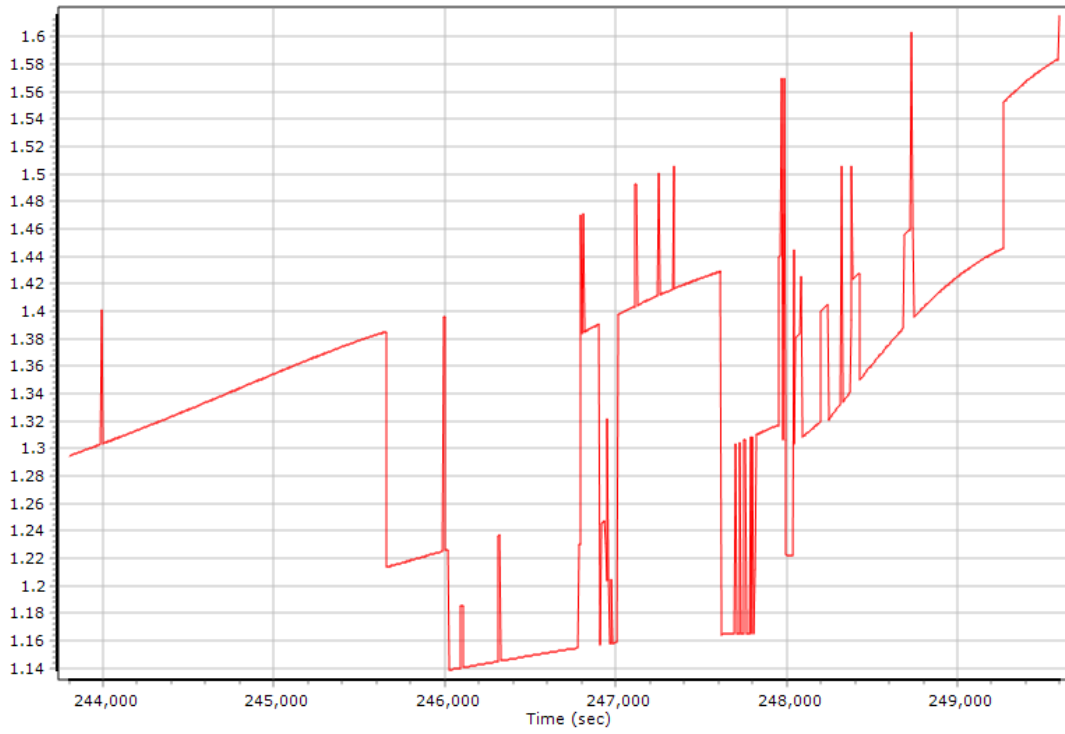
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



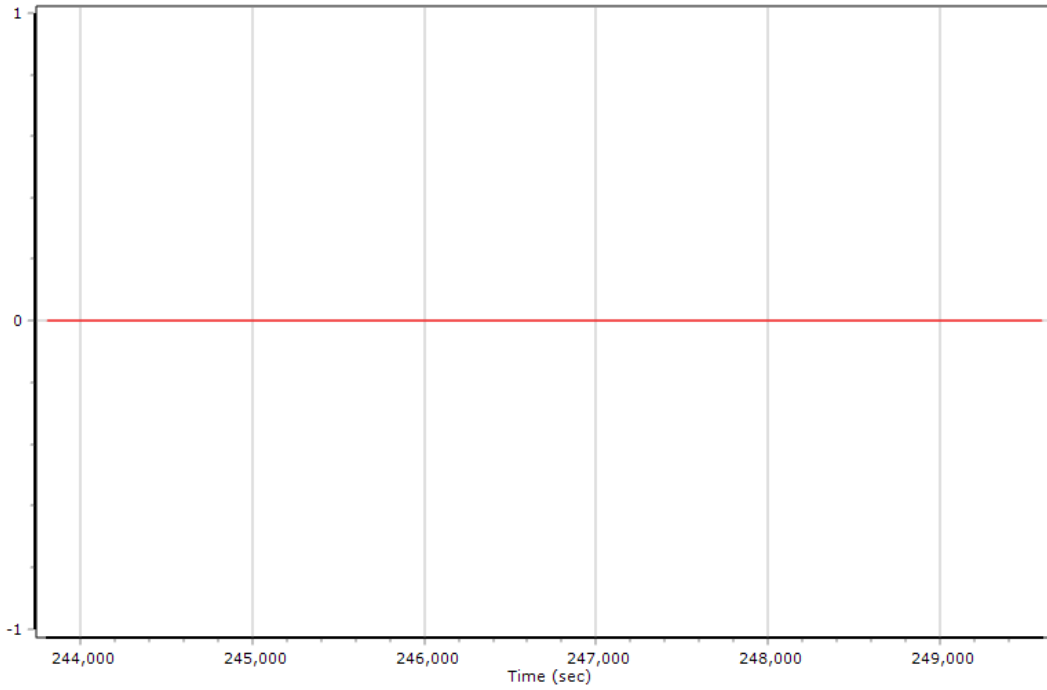
— North (m) — East (m) — Down (m) ◆ DR mode



PDOP

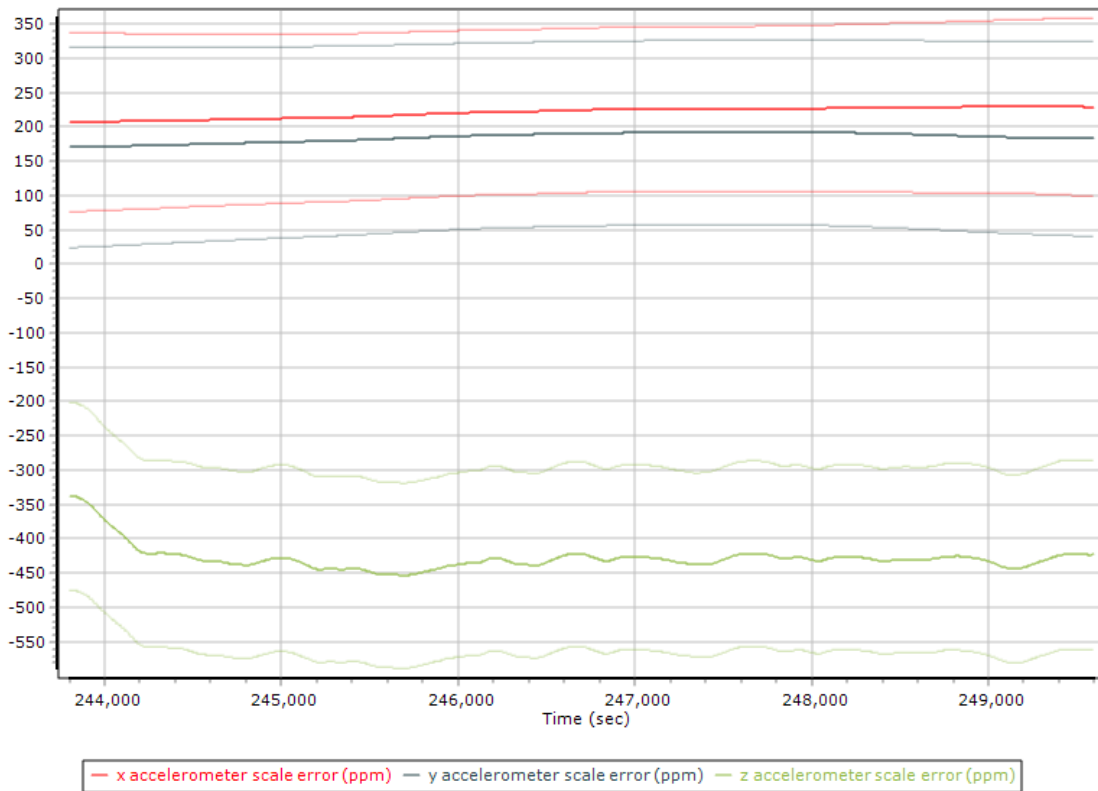
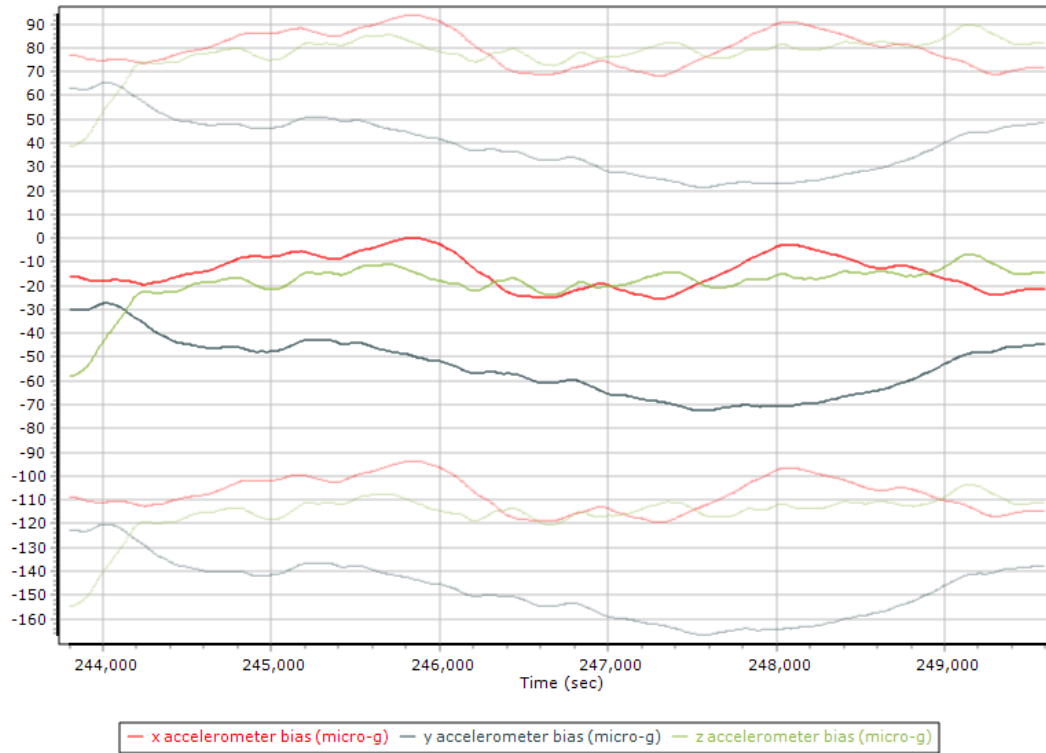


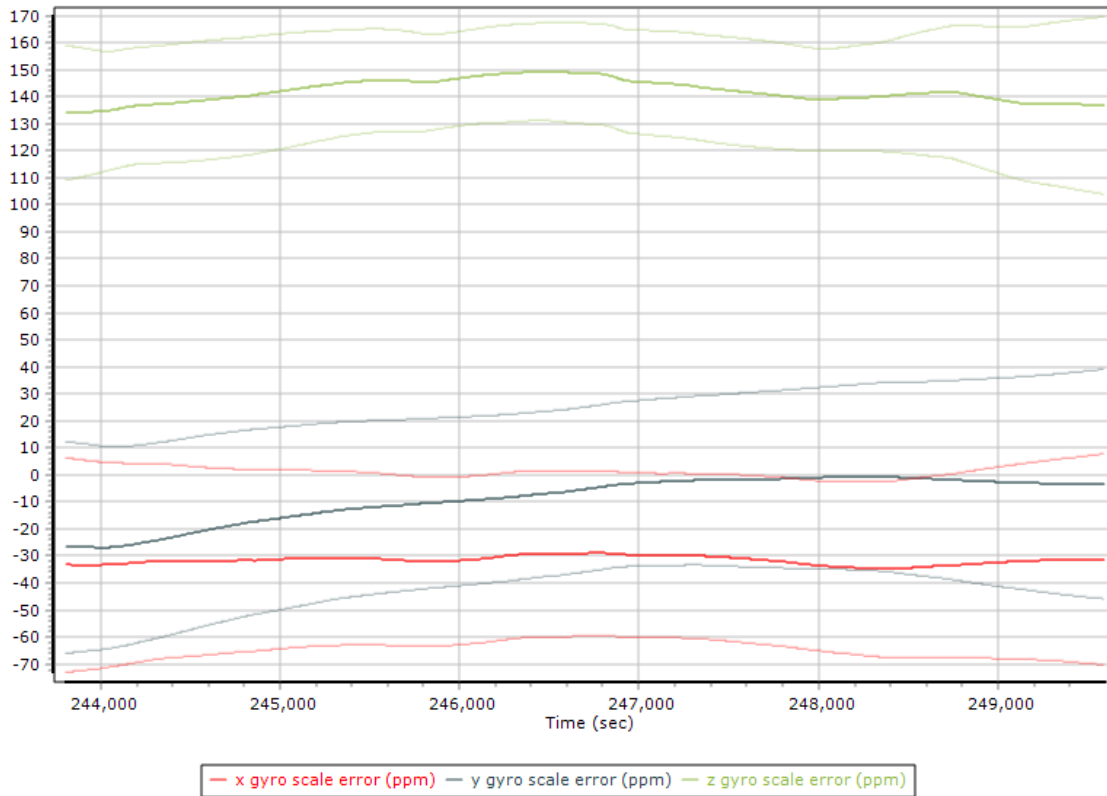
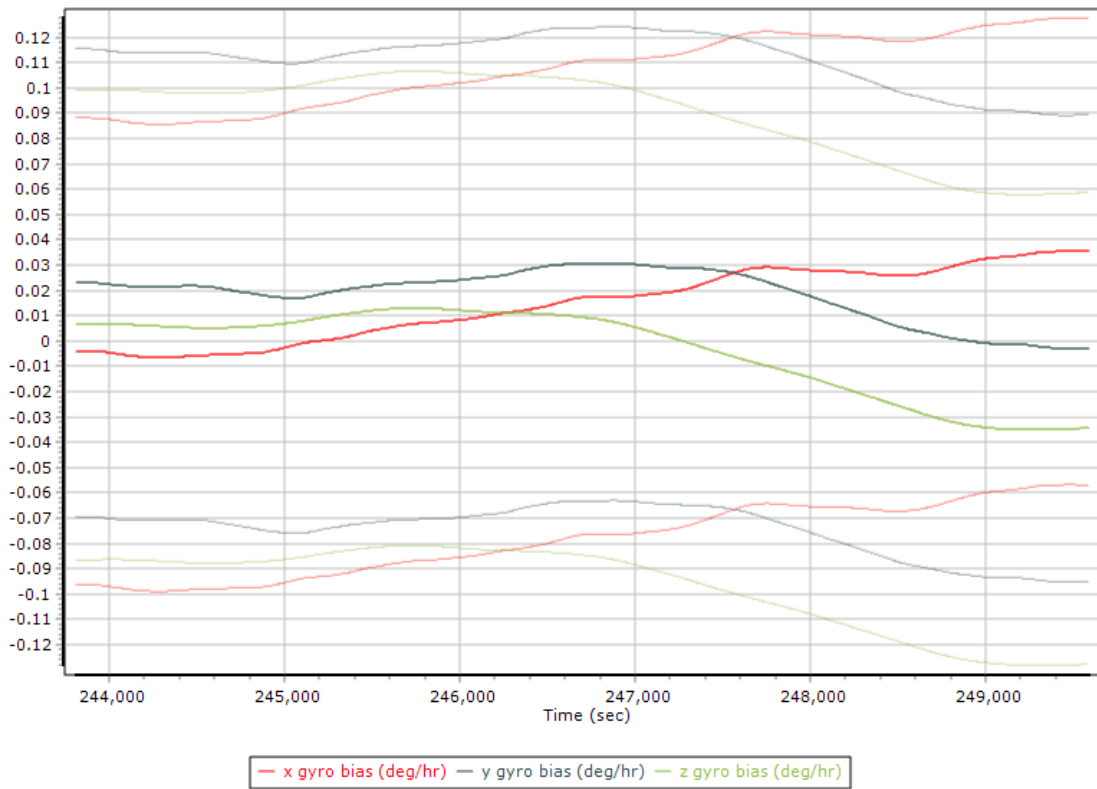
Processing mode



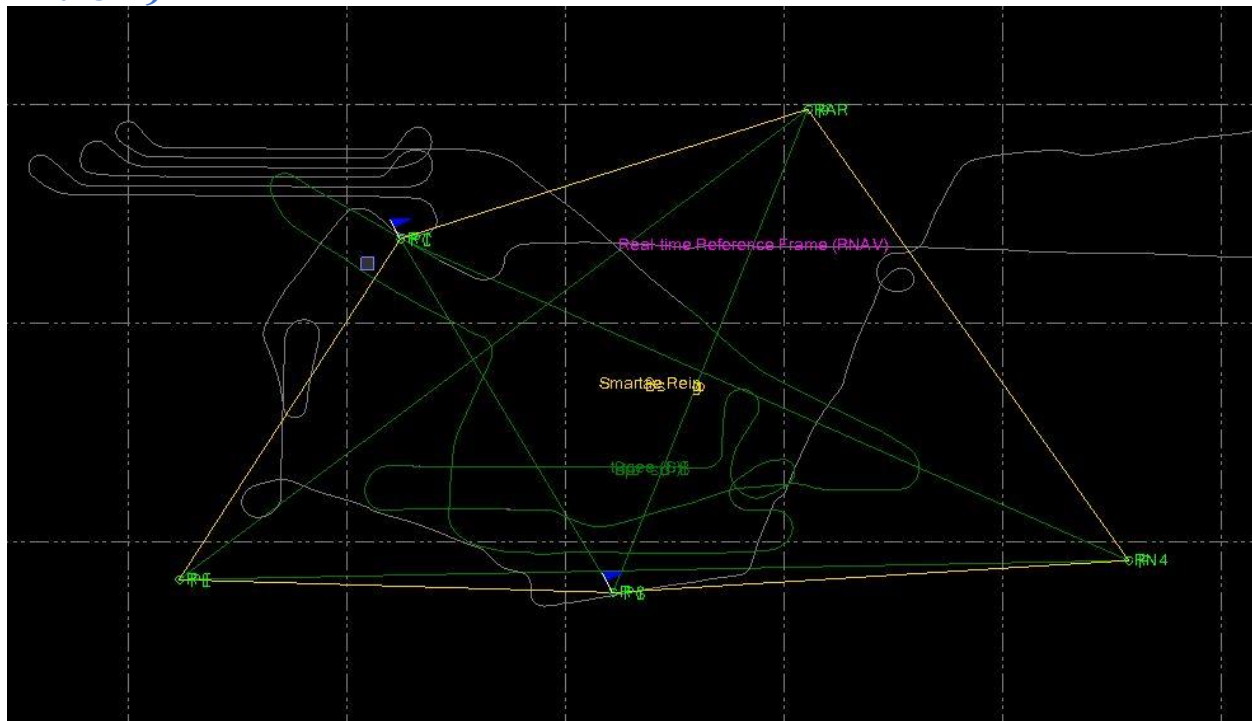
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





RBV18129A



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

Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.037 m	0.007 m	-0.985 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	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: 301474.930 Data Incr. (sec)

End: 305686.915 Output Record 0.005000

Entire time interval

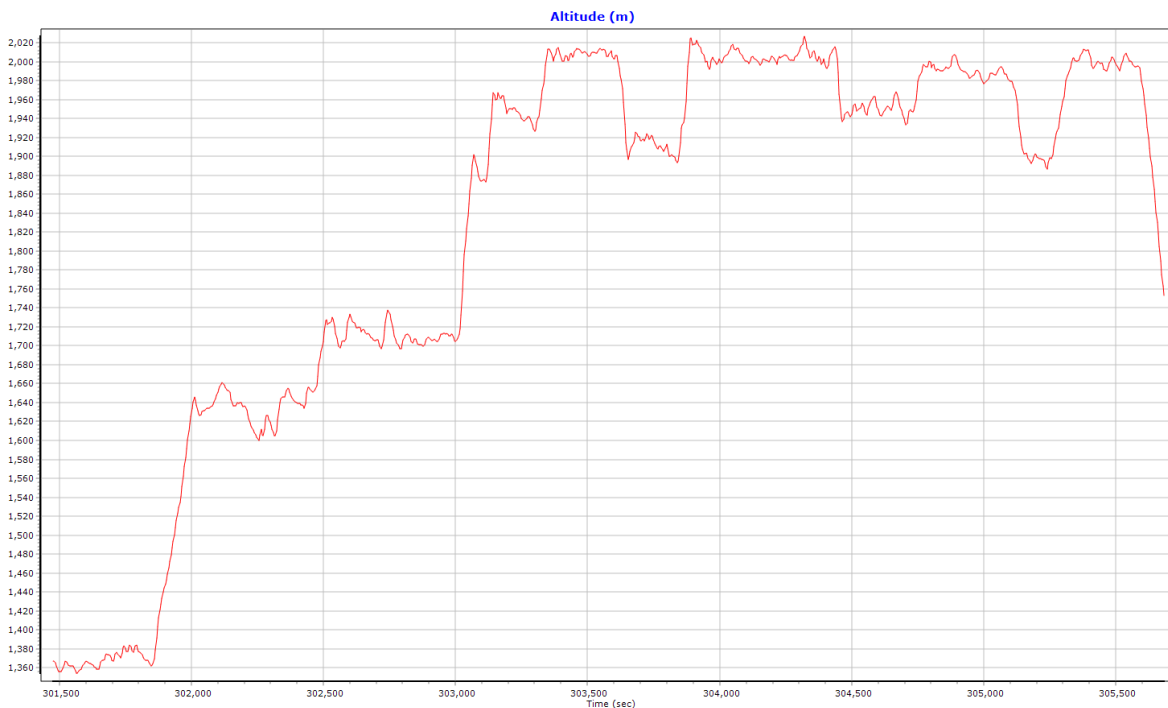
Seconds of start week

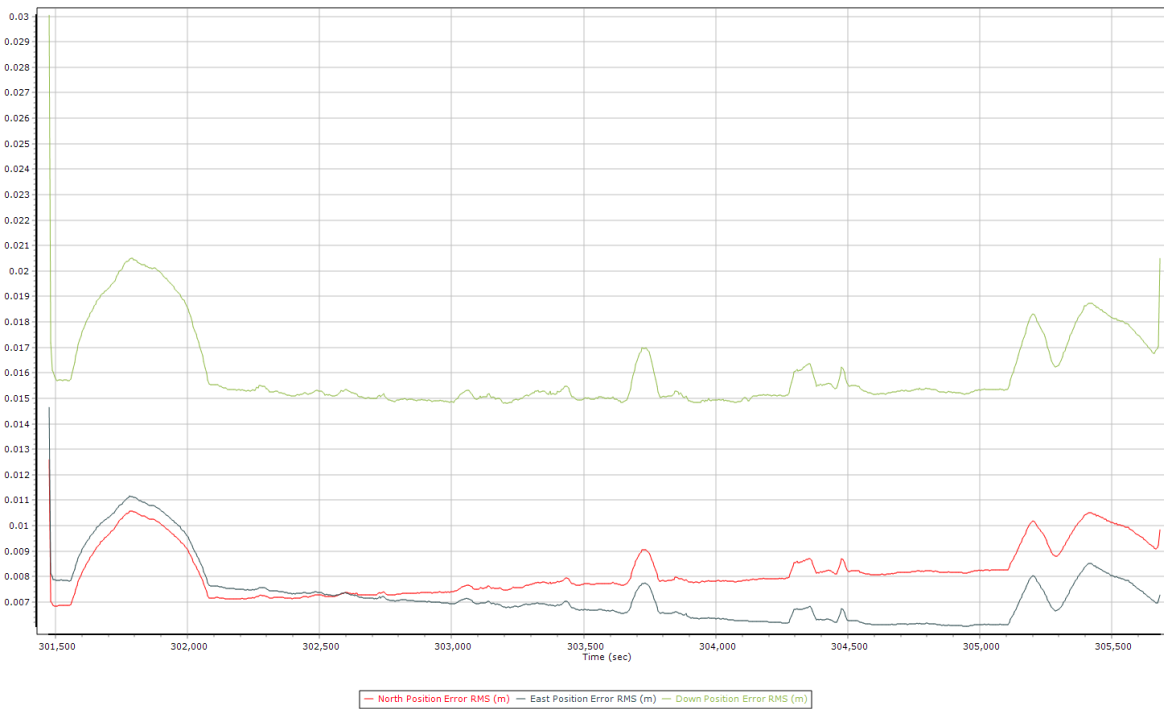
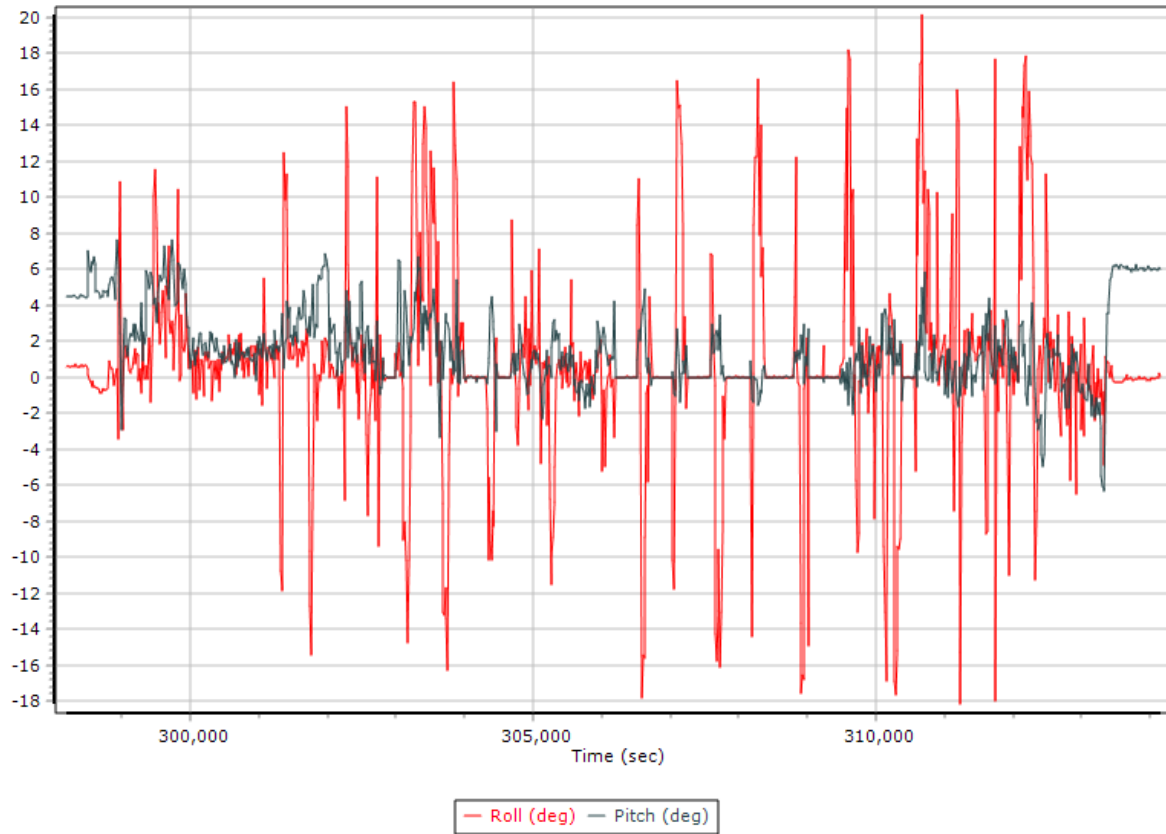
IMU 0.005000

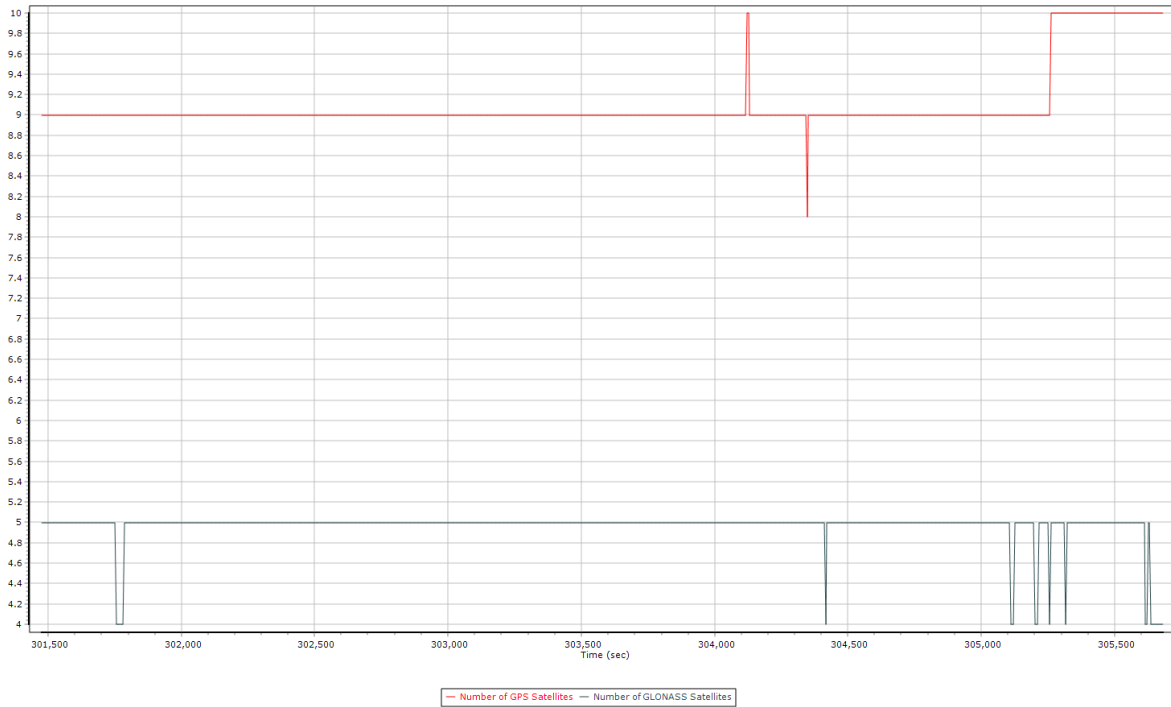
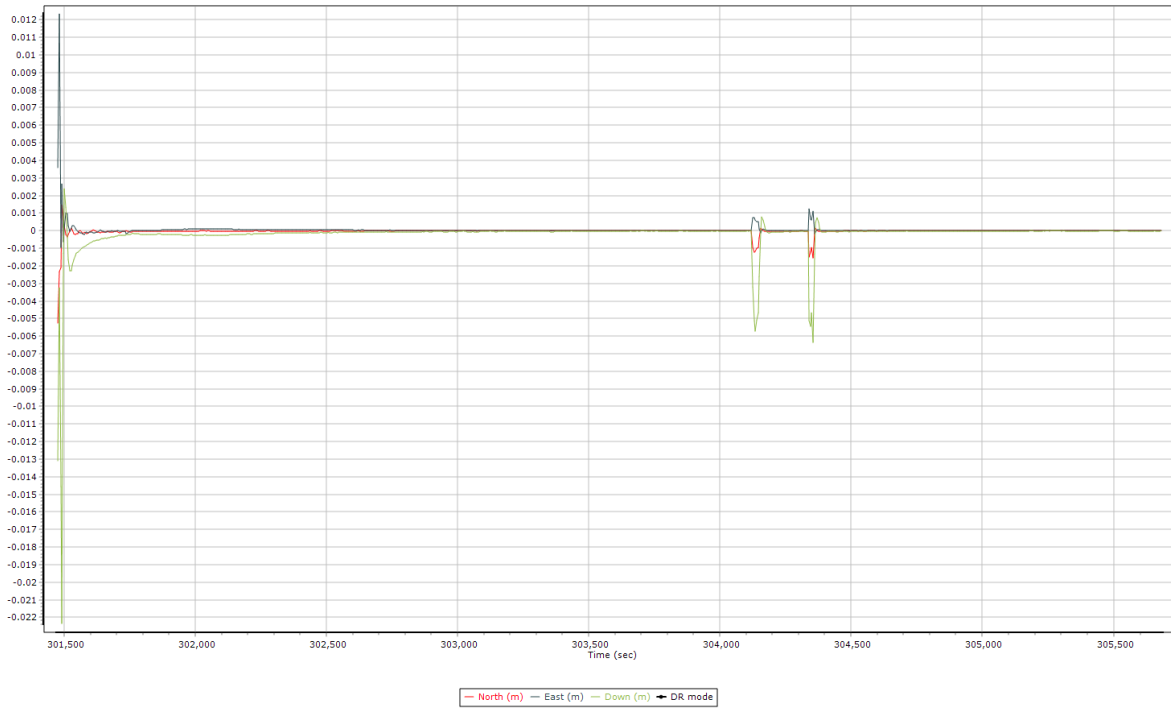
Primary GNSS 1.000000

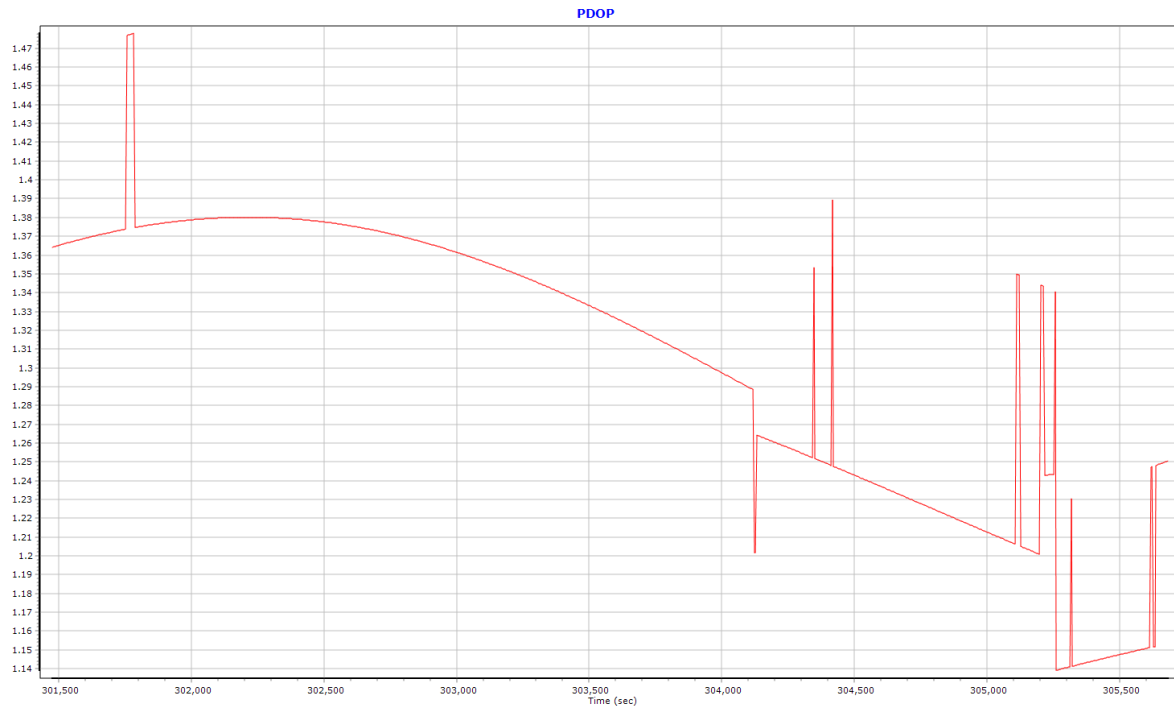
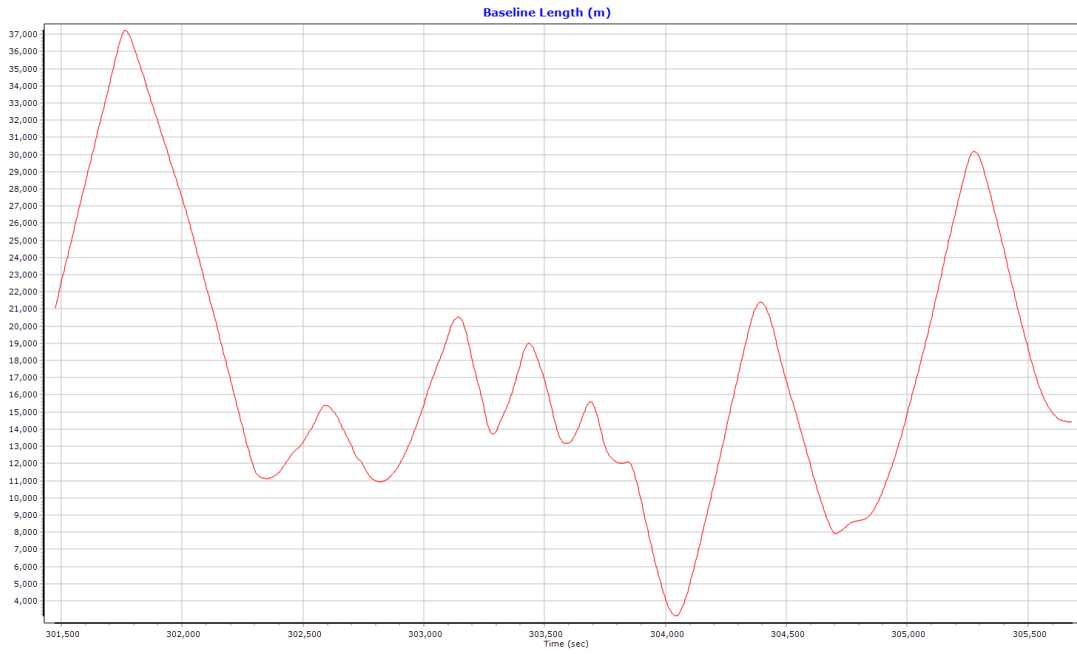
UTC Offset: 18.000

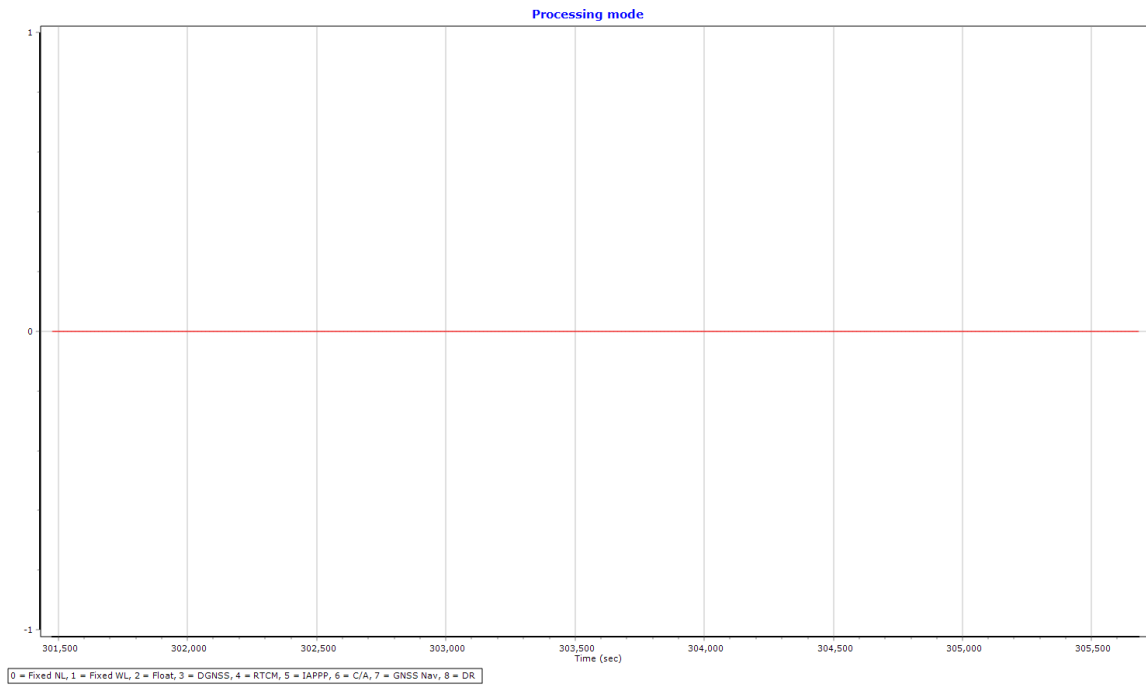
OK Cancel



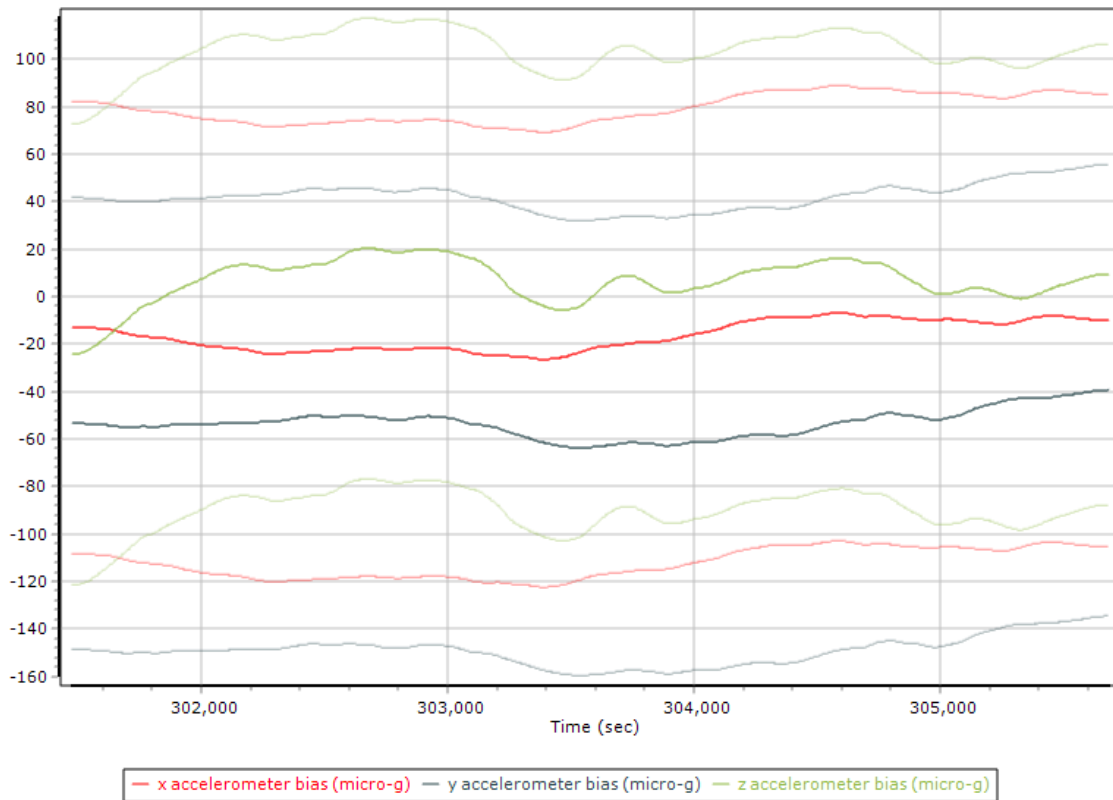


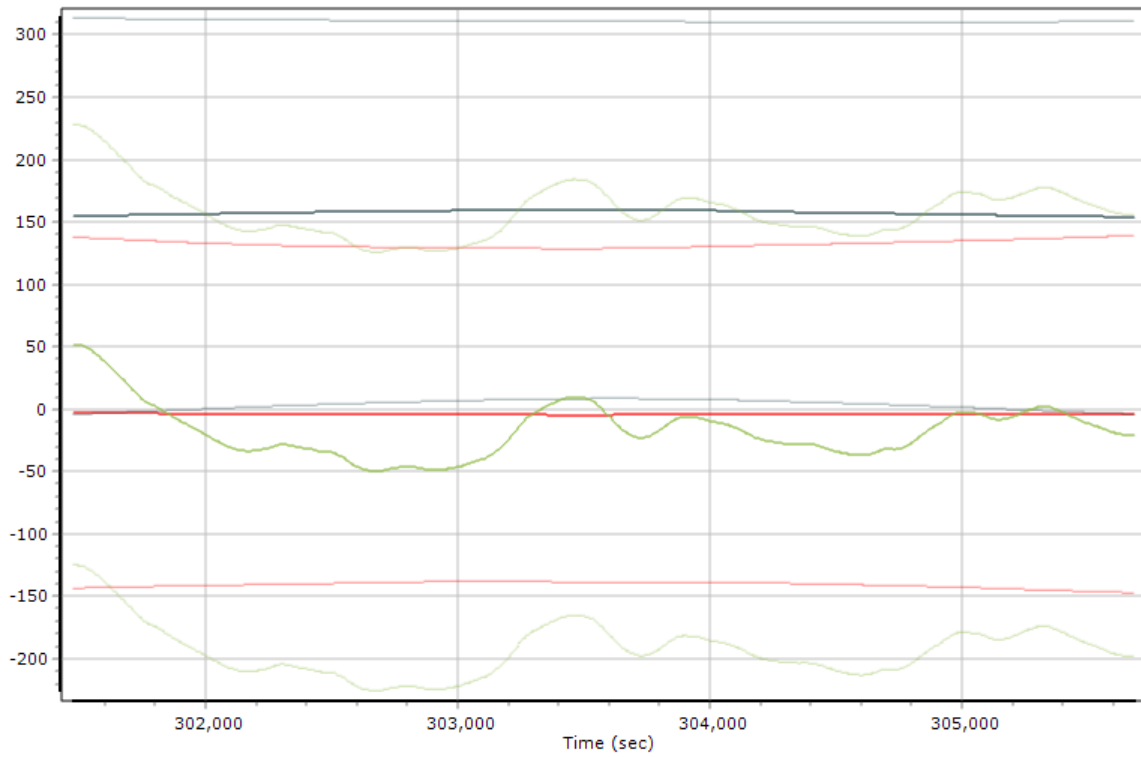




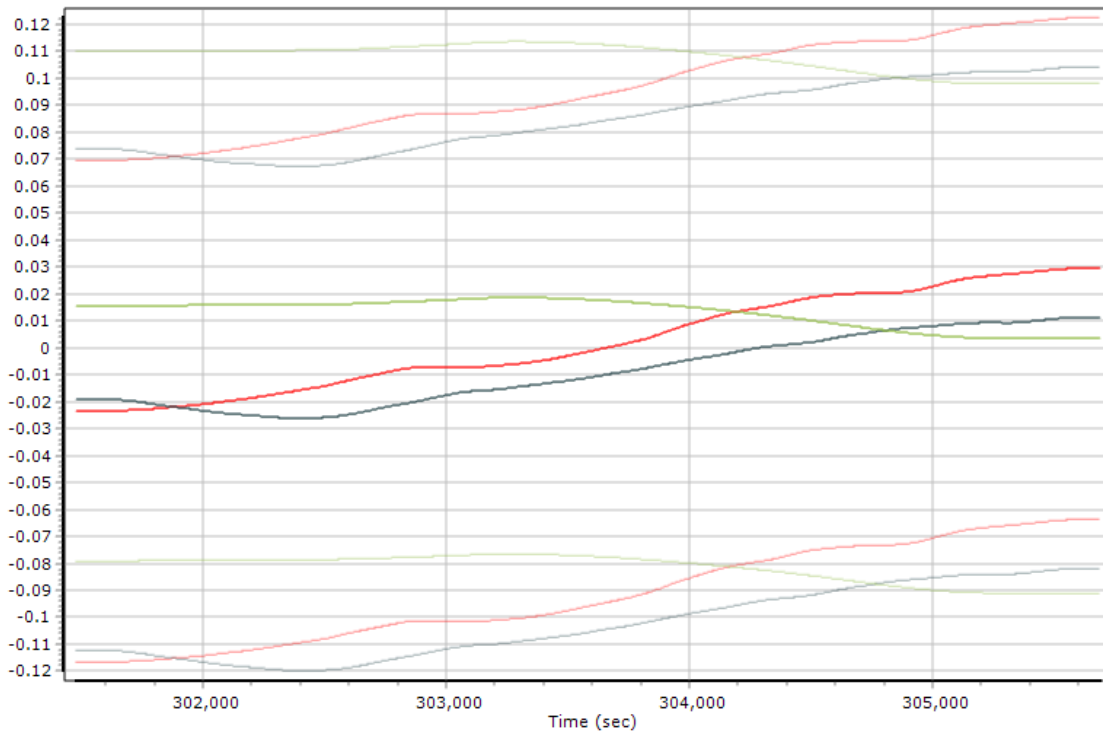


Sensor Errors

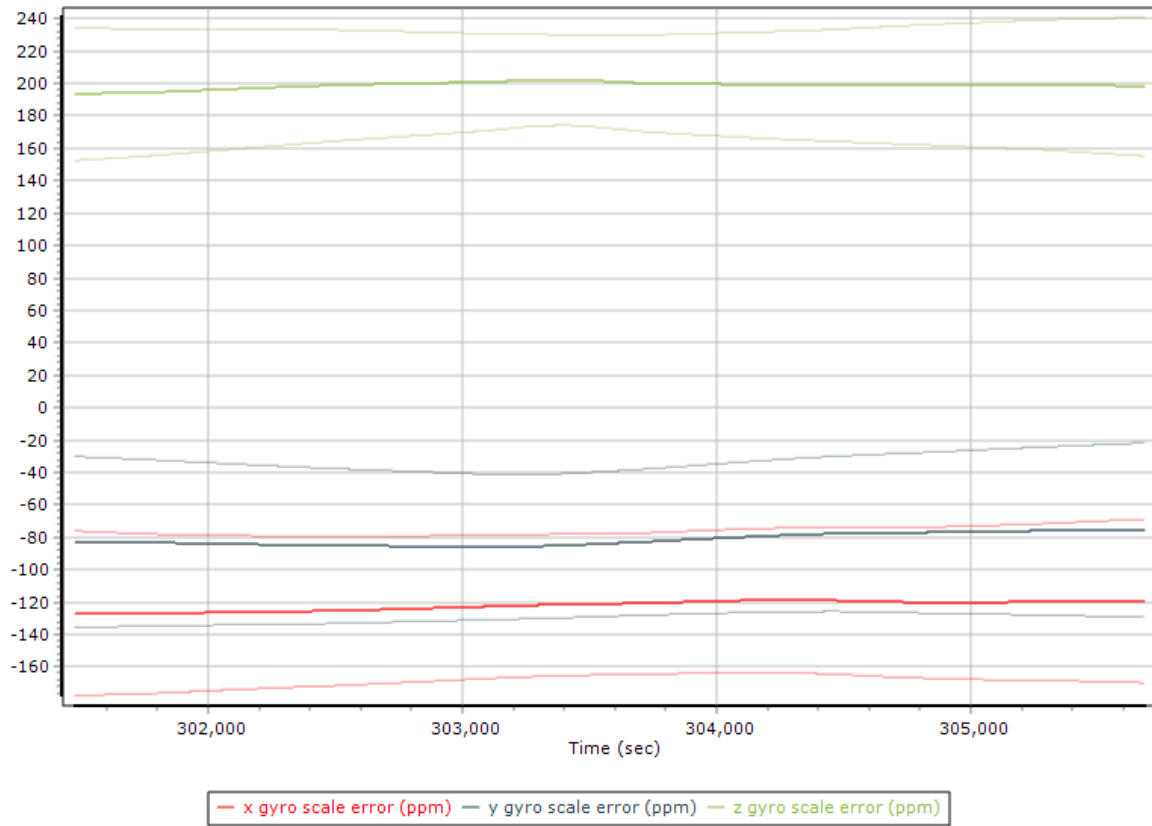




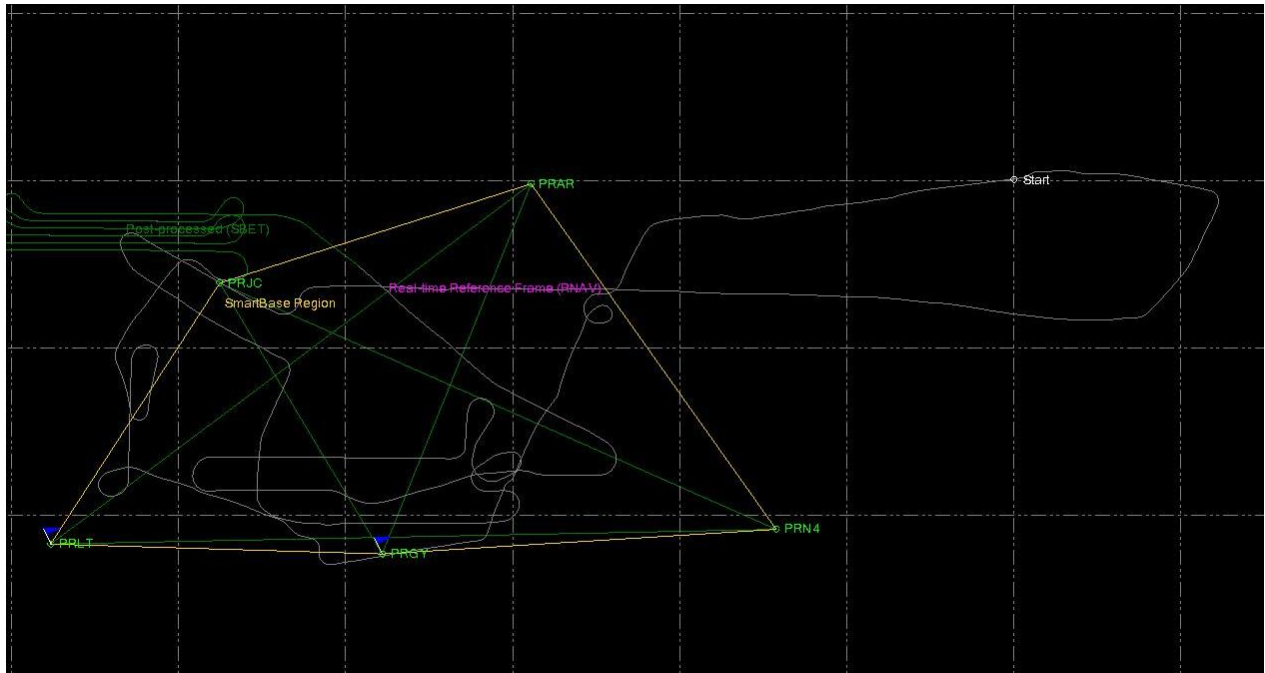
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

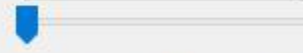


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



RBV18129A2

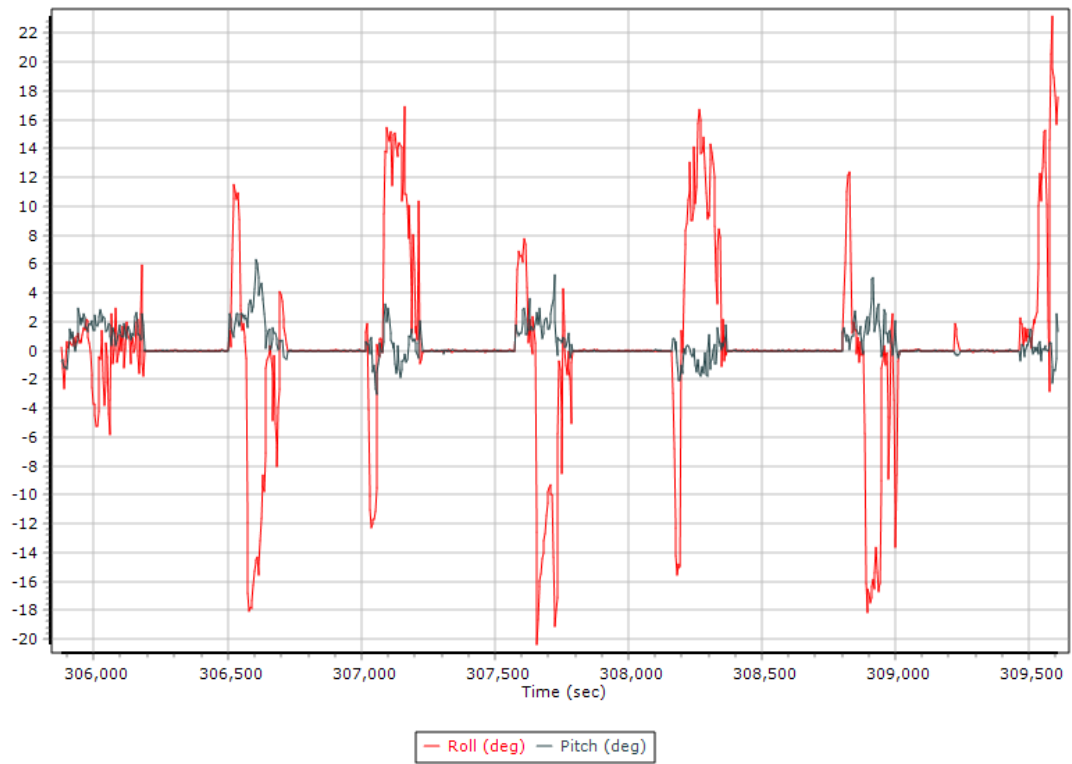
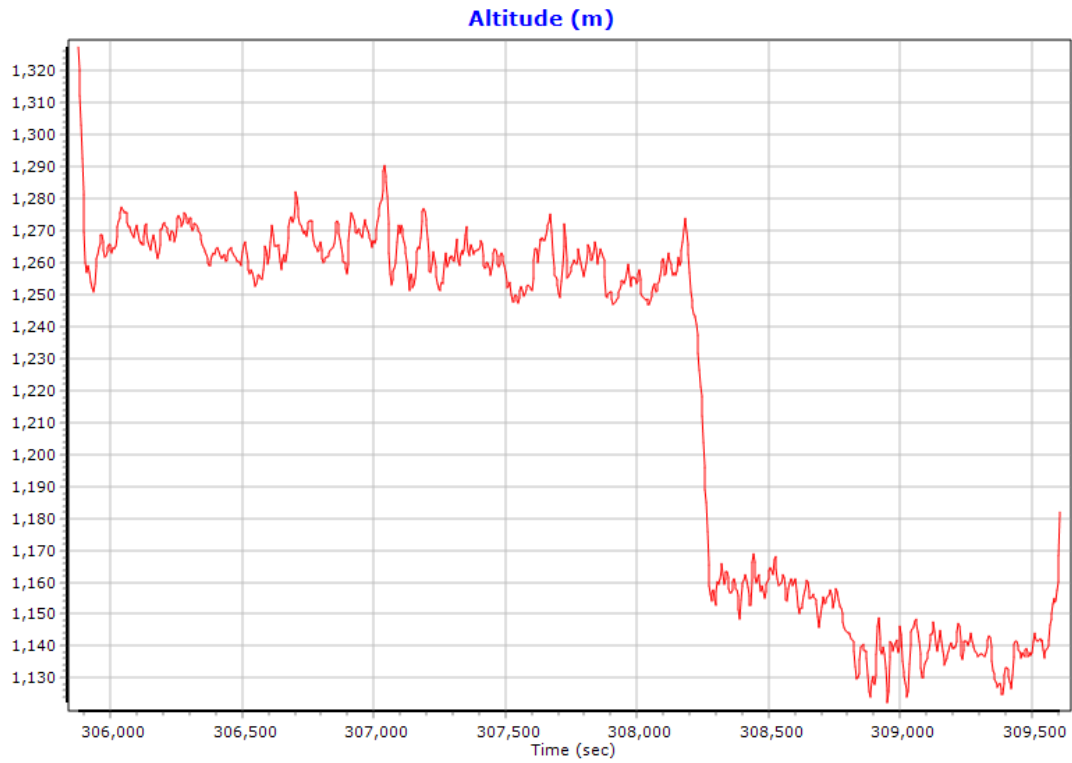


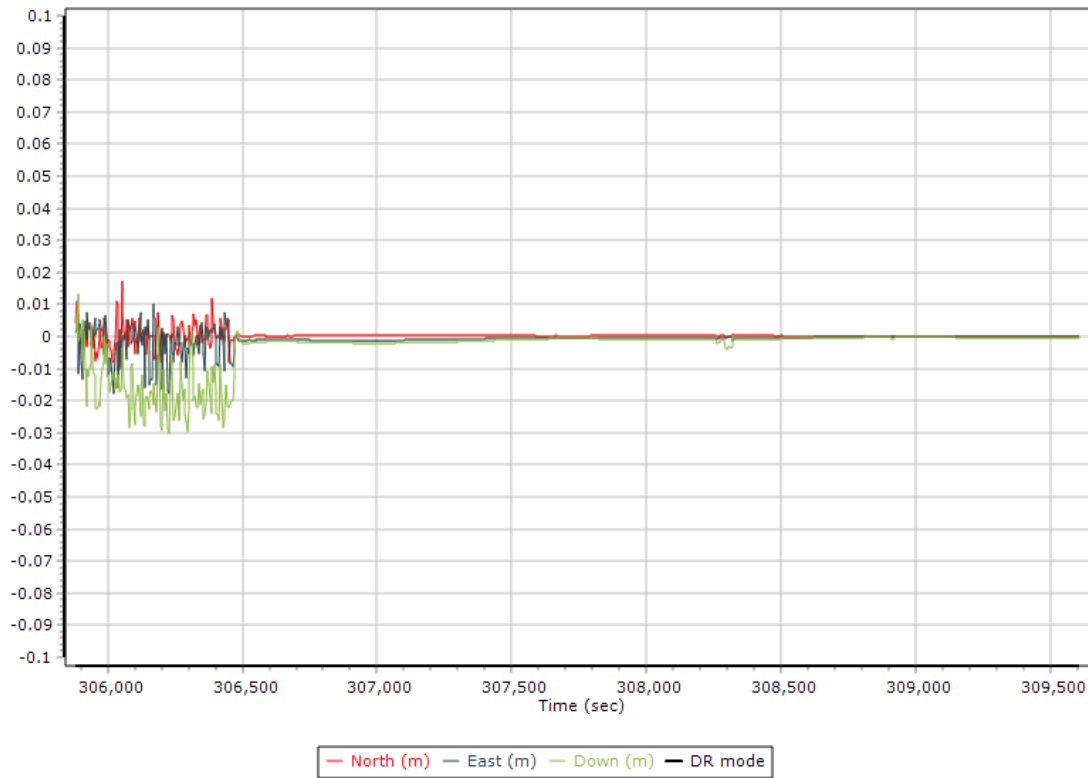
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 deg"/>
Stabilized Mount to Primary GNSS Lever Arm		Aircraft to Stabilized Mount Mounting Angles	
X	<input type="text" value="-0.037 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="0.007 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.985 m"/>	Z	<input type="text" value="0.000 deg"/>
Standard Deviation			
	<3cm 10cm 50cm 1m 10m		

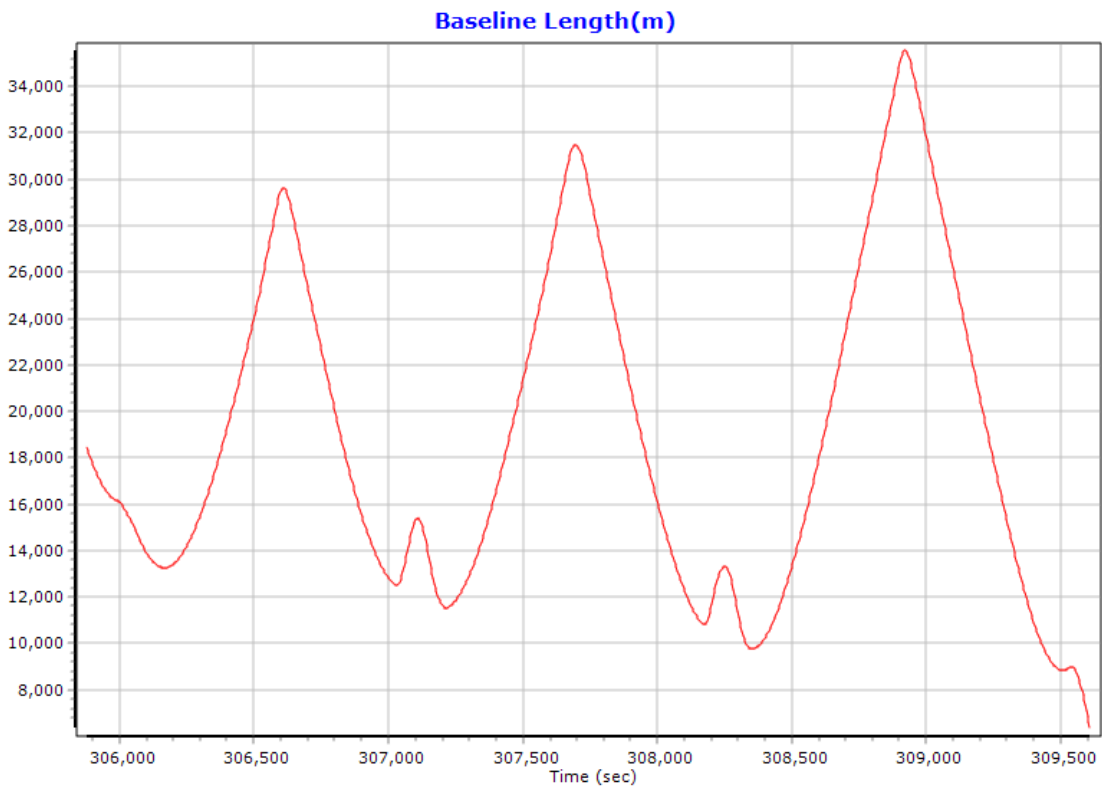
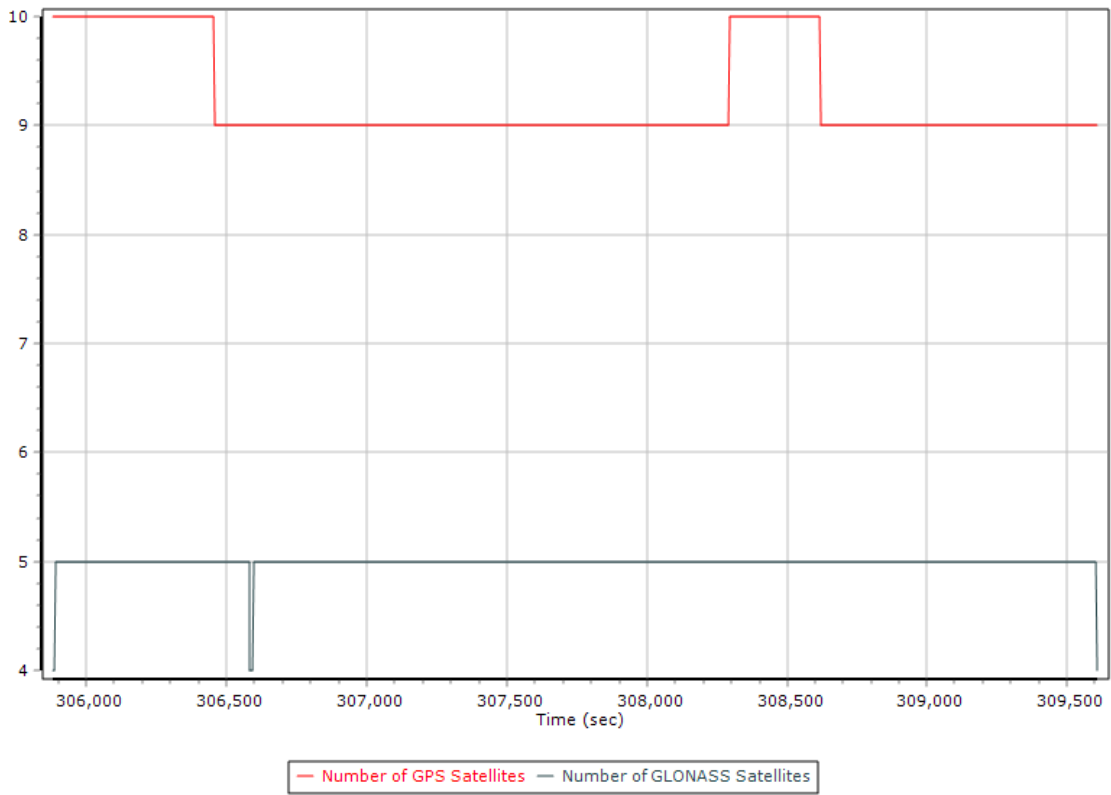
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

Timing

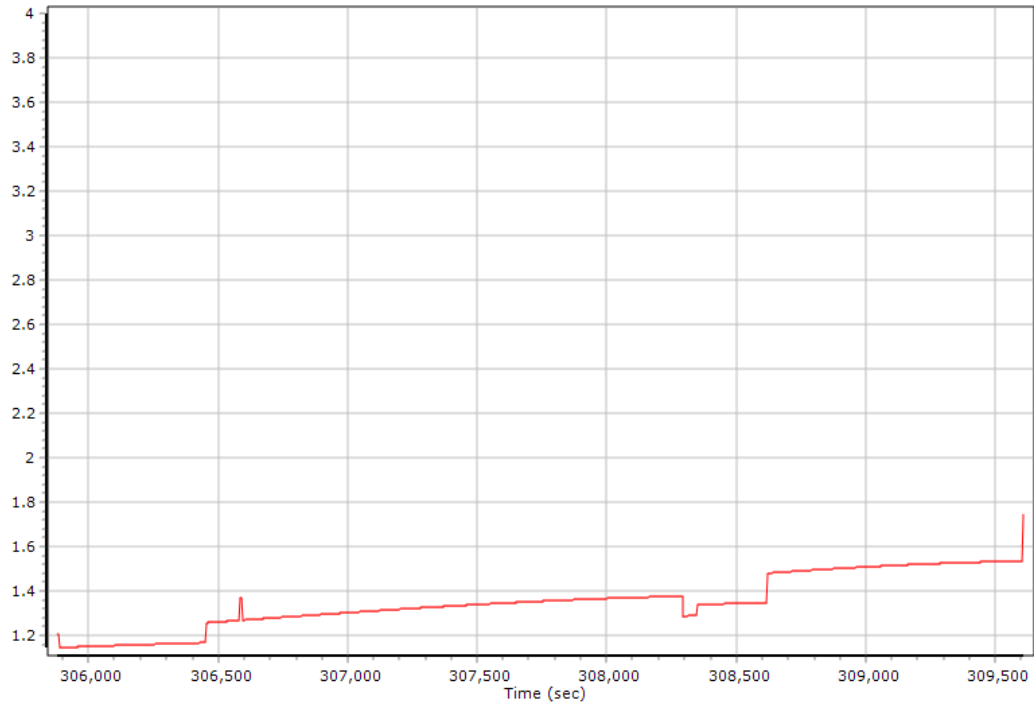
Start	<input type="text" value="305877.870"/>	Data	Incr. (sec)	^
End	<input type="text" value="309610.312"/>	Output Record	0.005000	
<input type="checkbox"/> Entire time interval		IMU	0.005000	
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000	v
UTC Offset	<input type="text" value="18.000"/>			



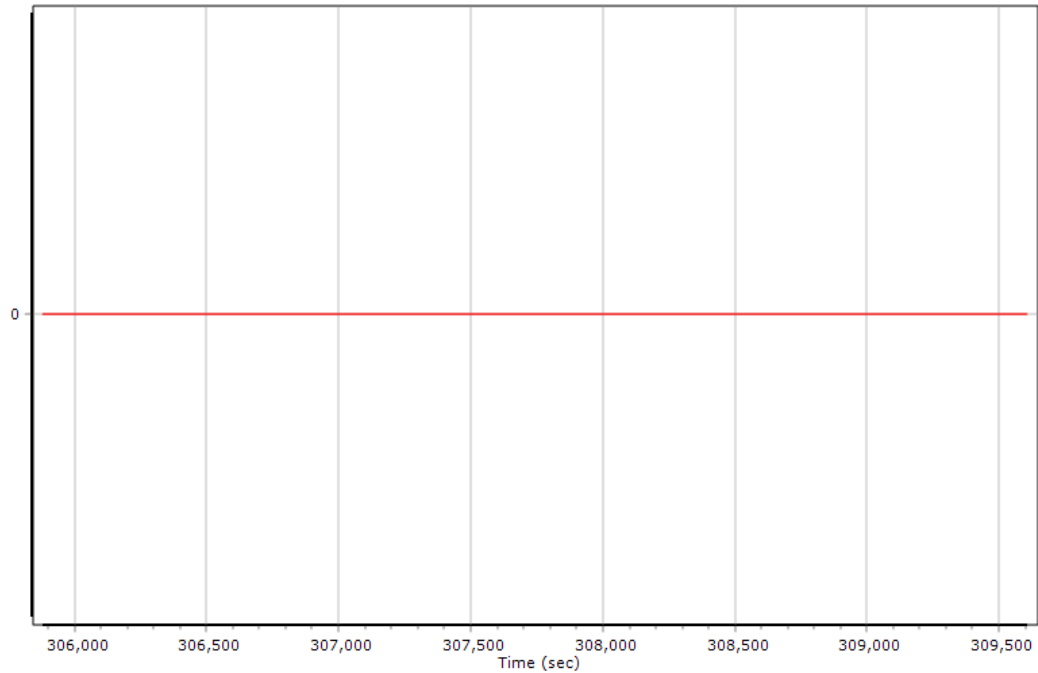




PDOP

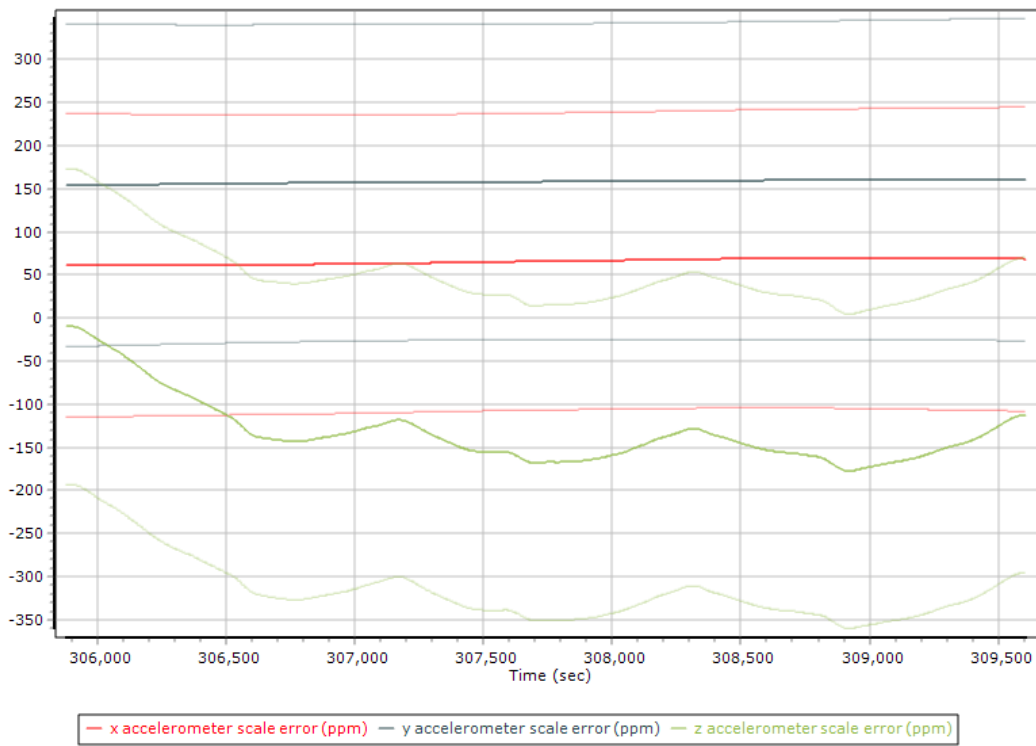
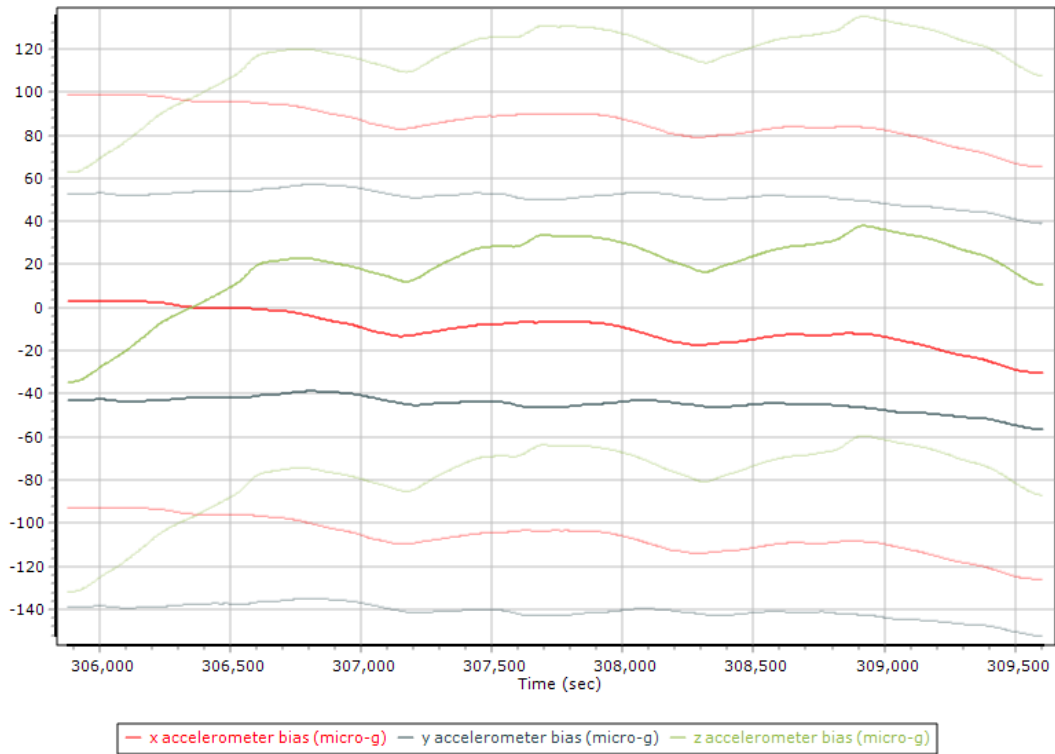


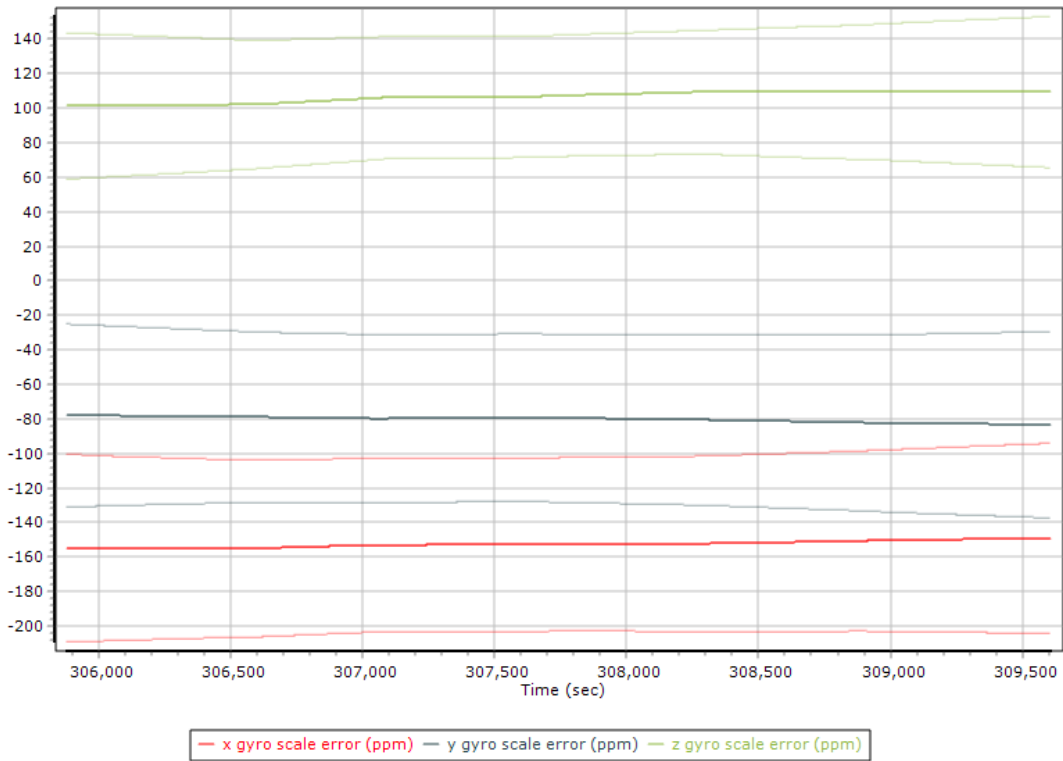
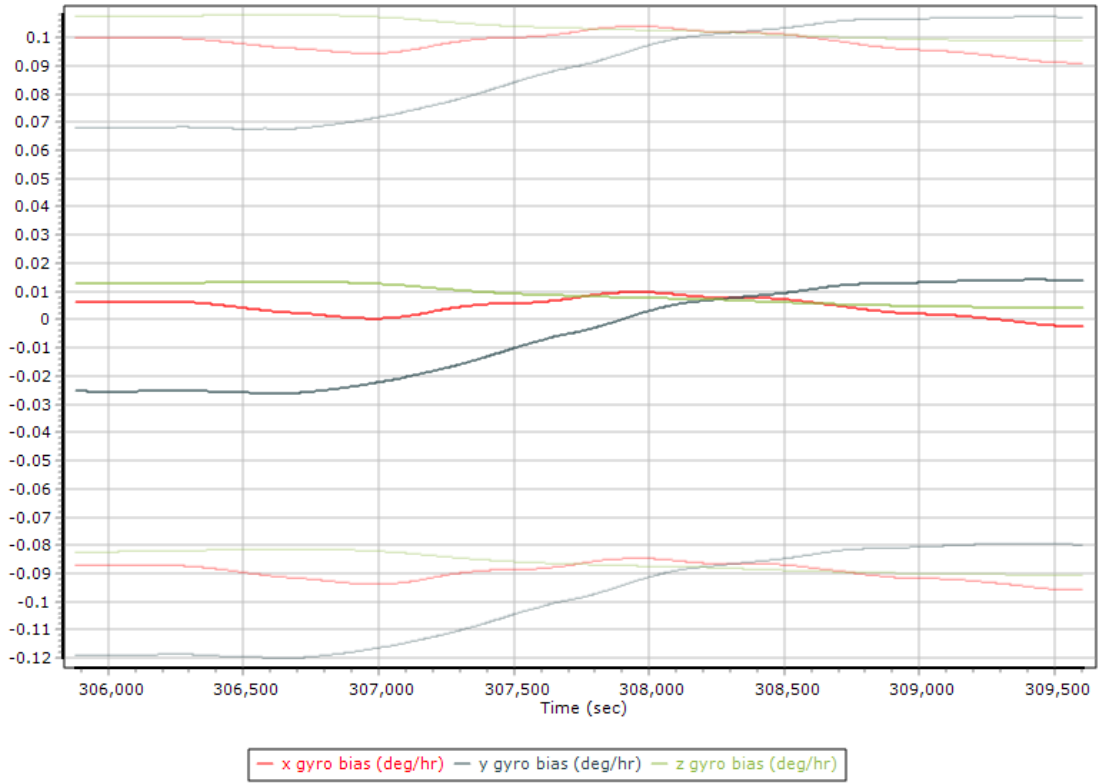
Processing Mode



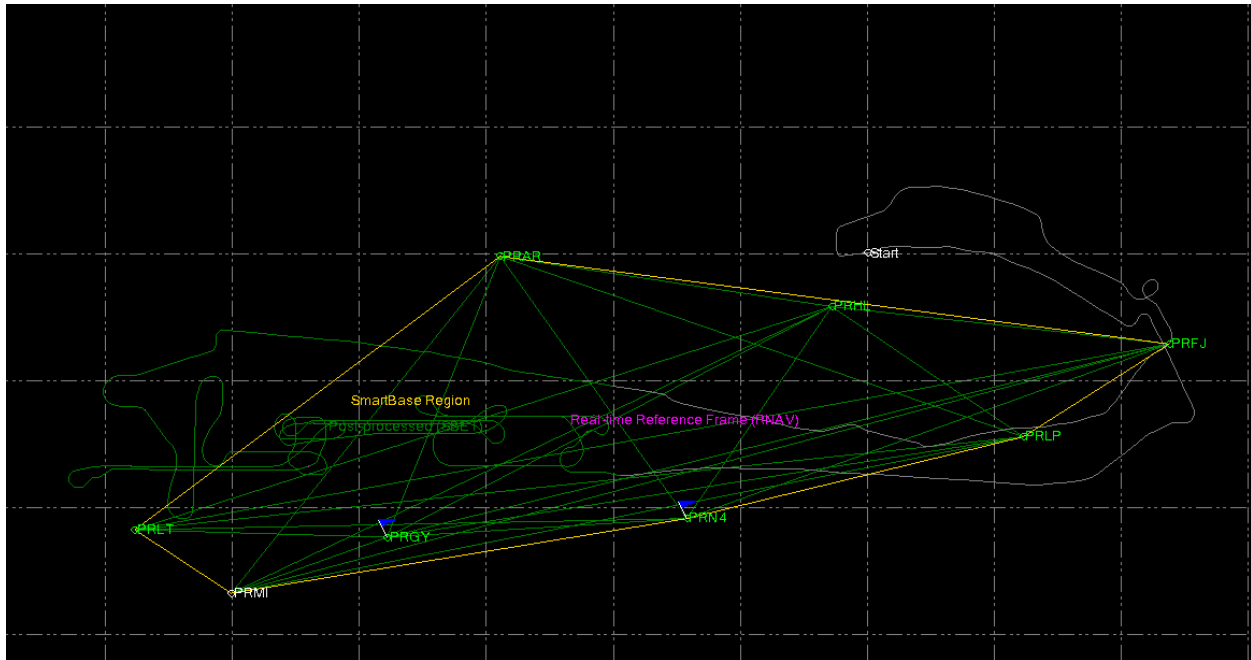
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





RBV18130A



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

Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.037 m	0.007 m	-0.985 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	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

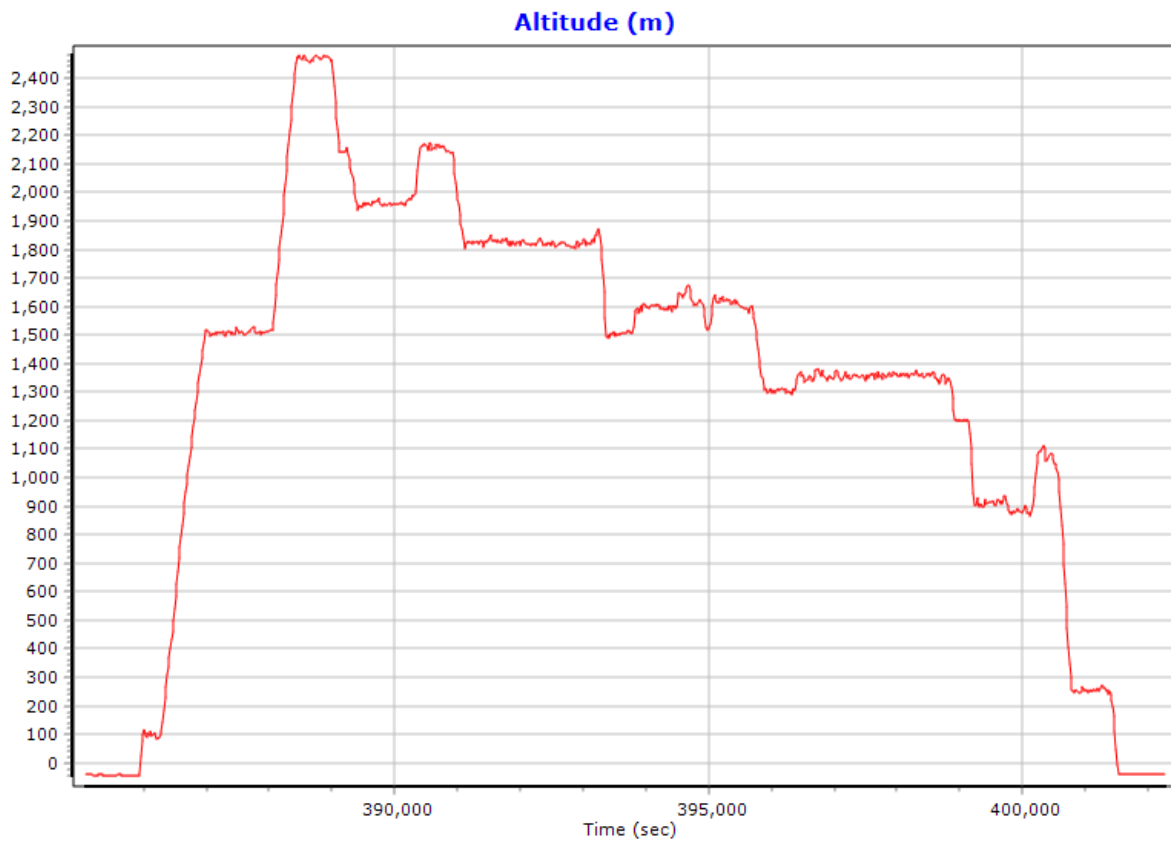
Start: 388991.047
End: 398320.234

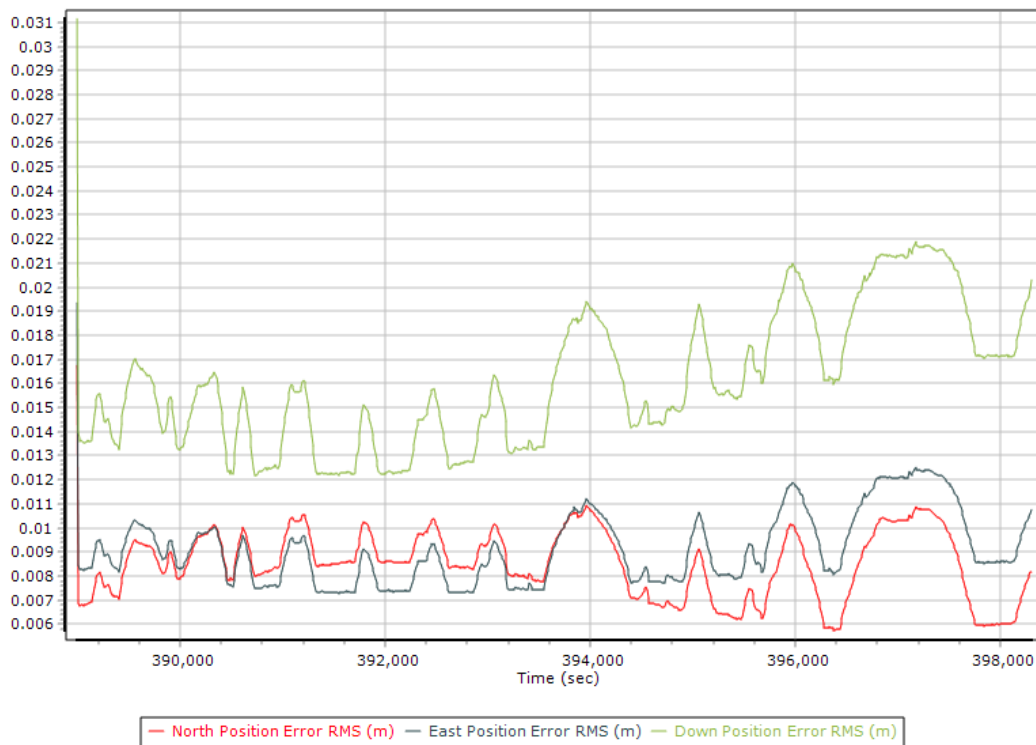
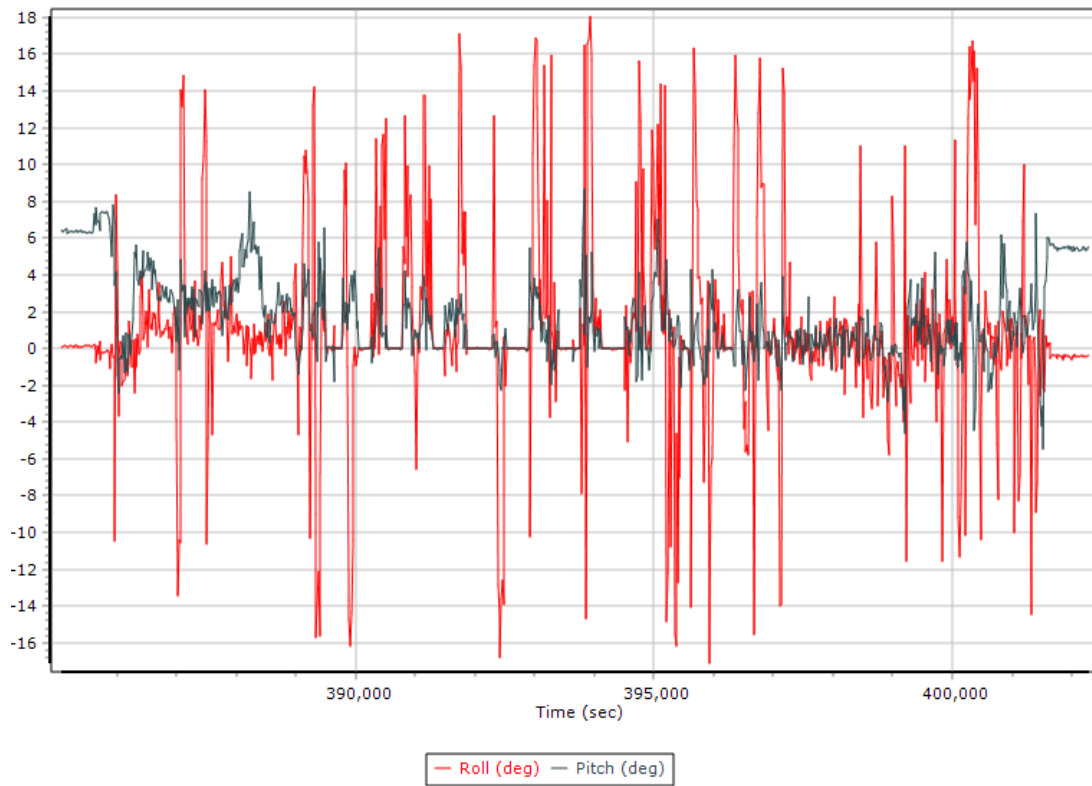
Entire time interval
 Seconds of start week

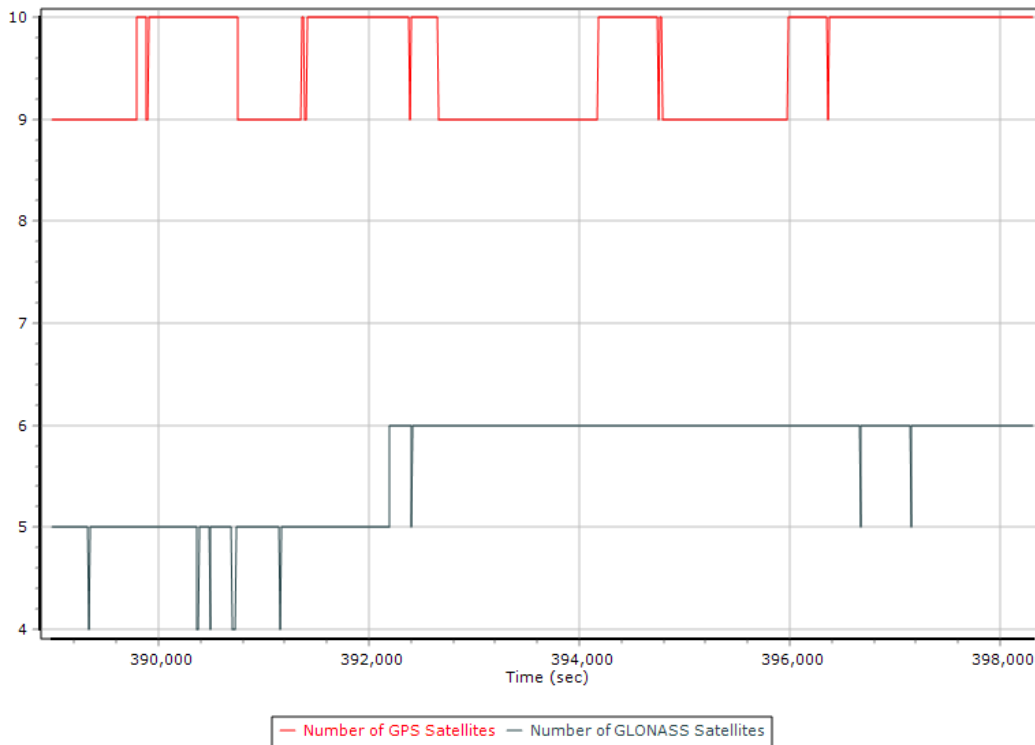
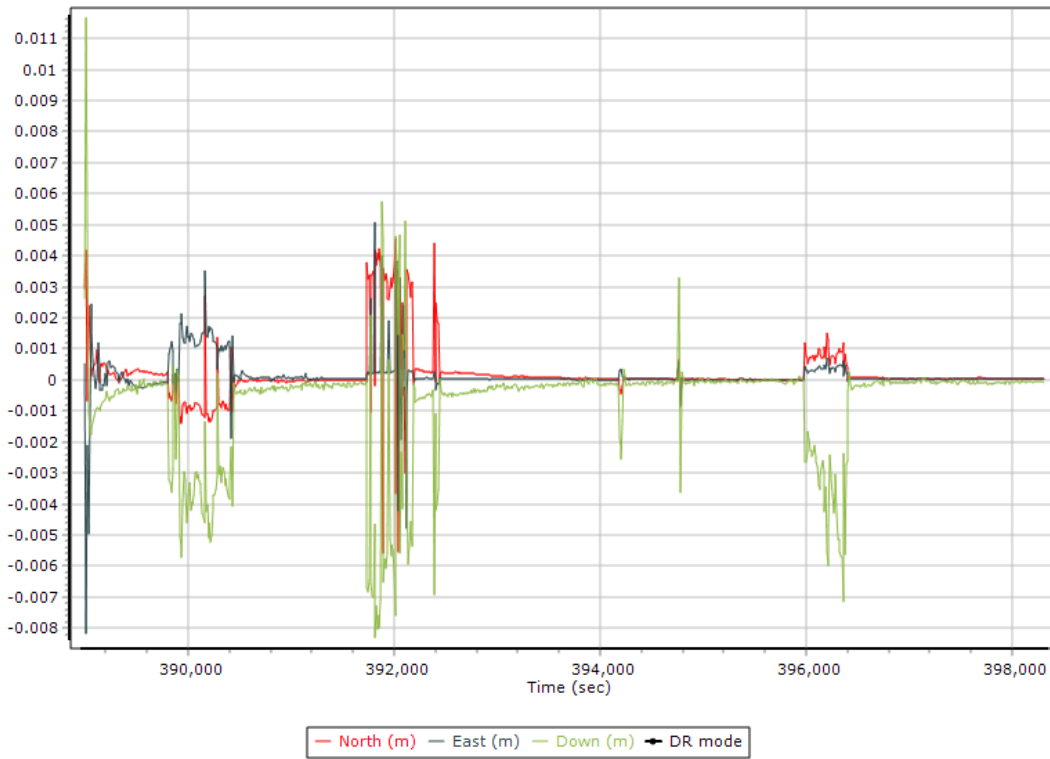
UTC Offset: 18.000

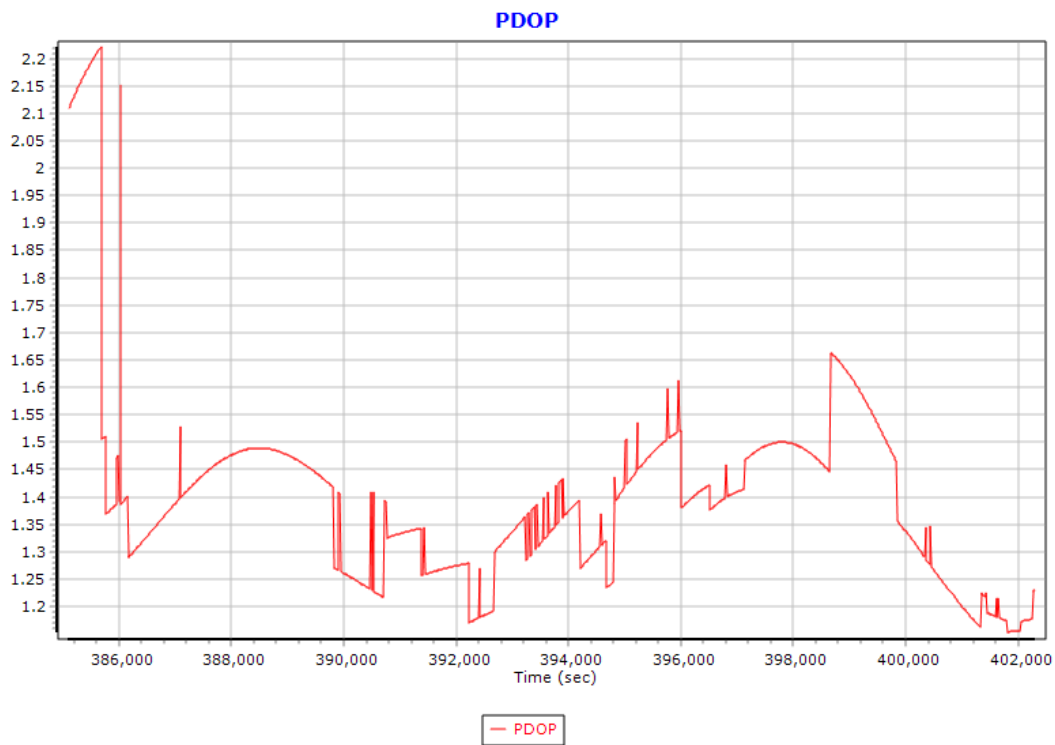
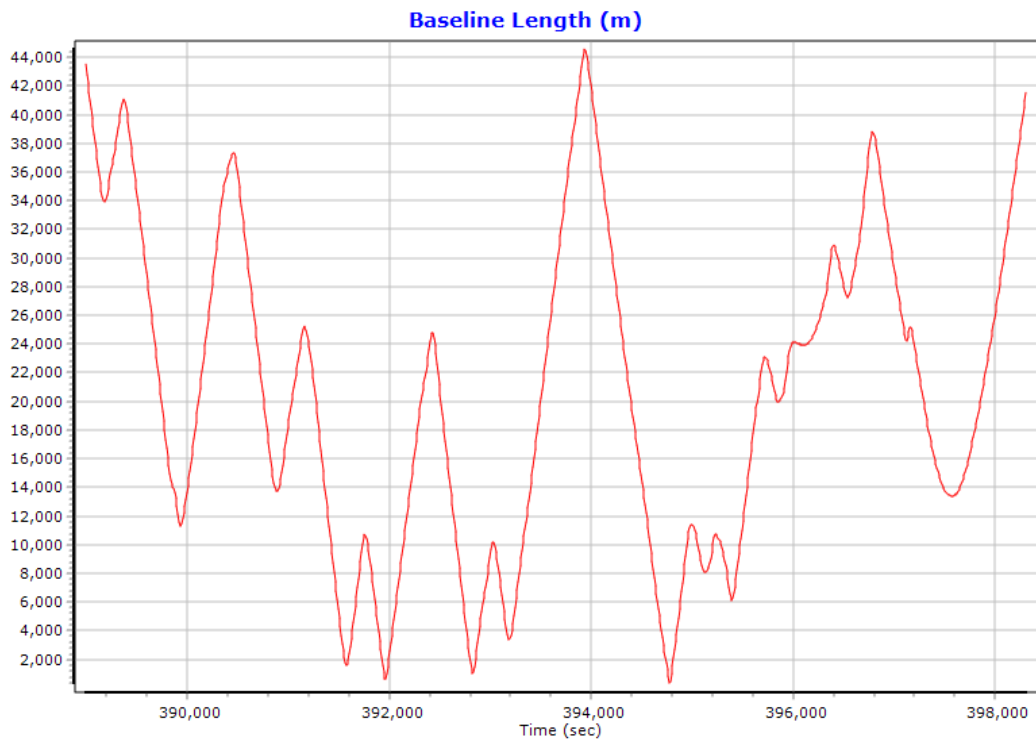
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel

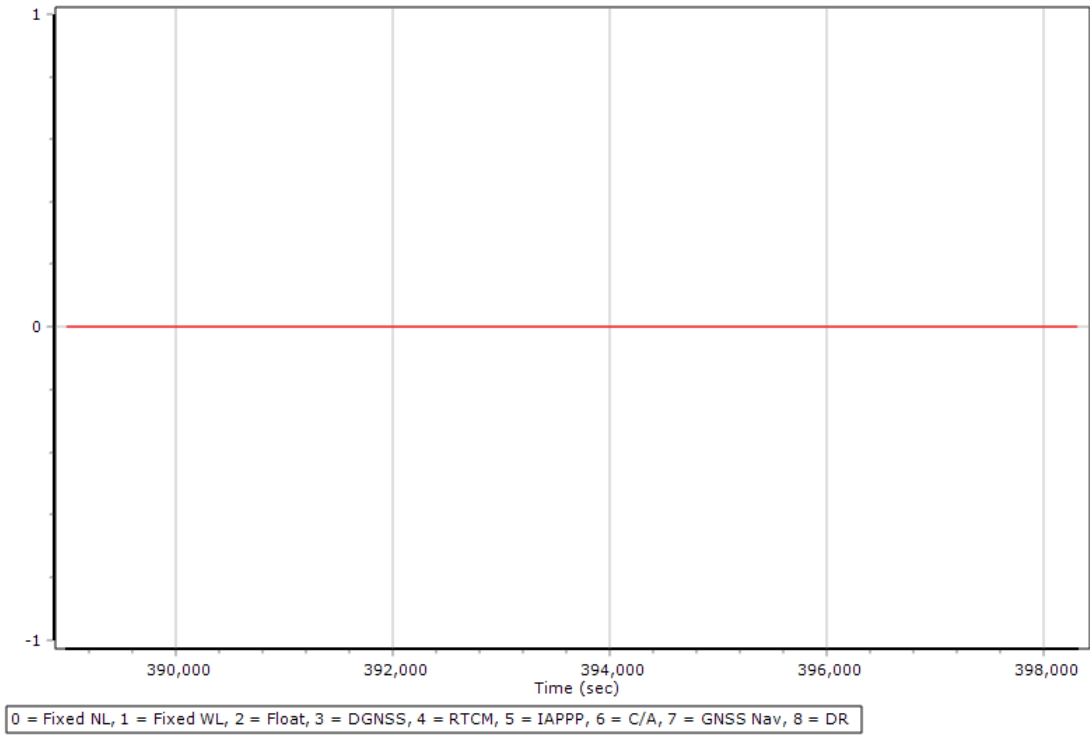




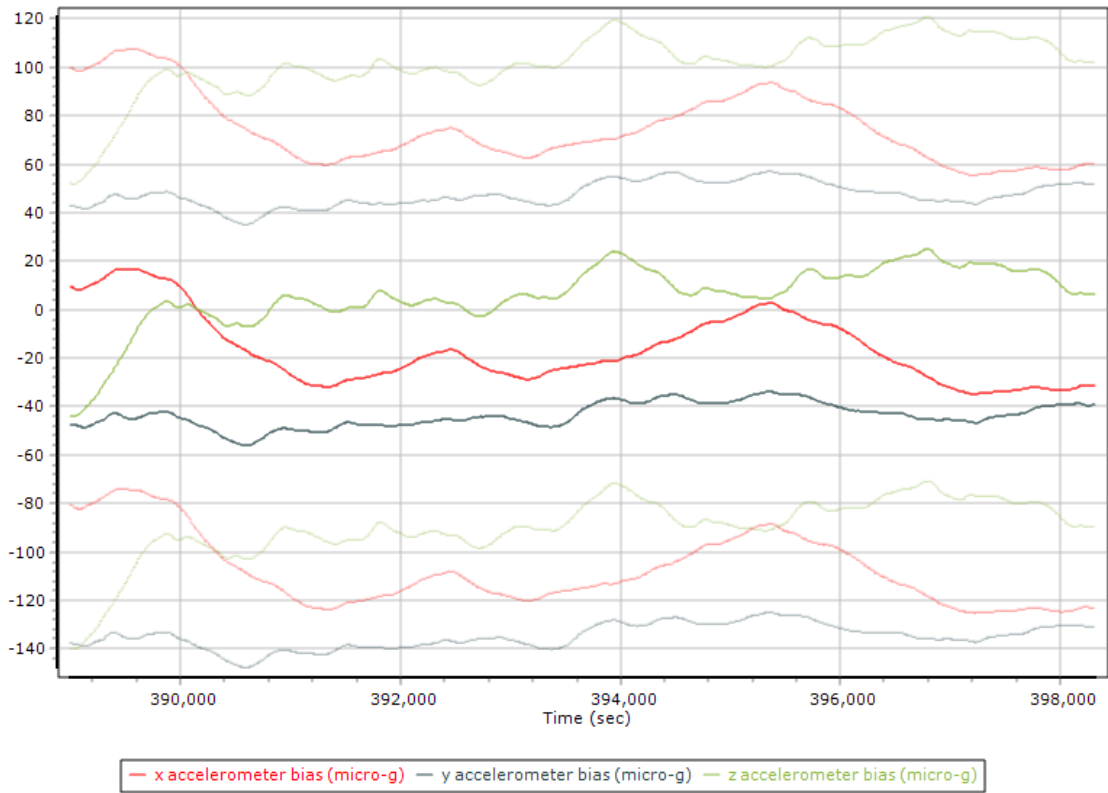


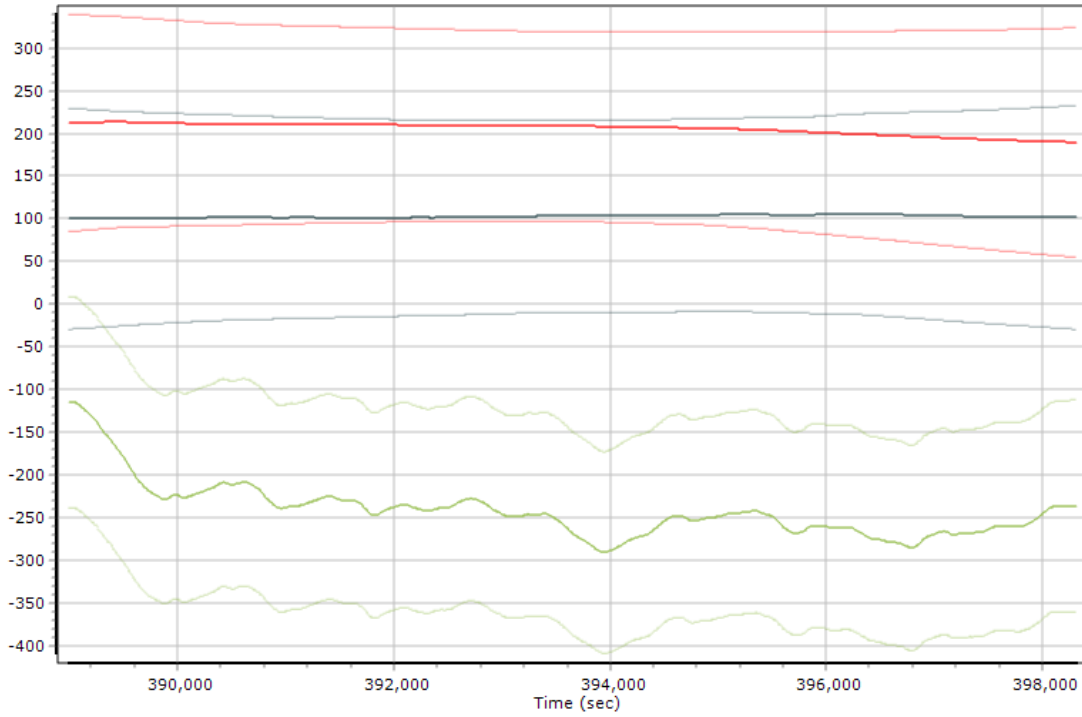


Processing mode

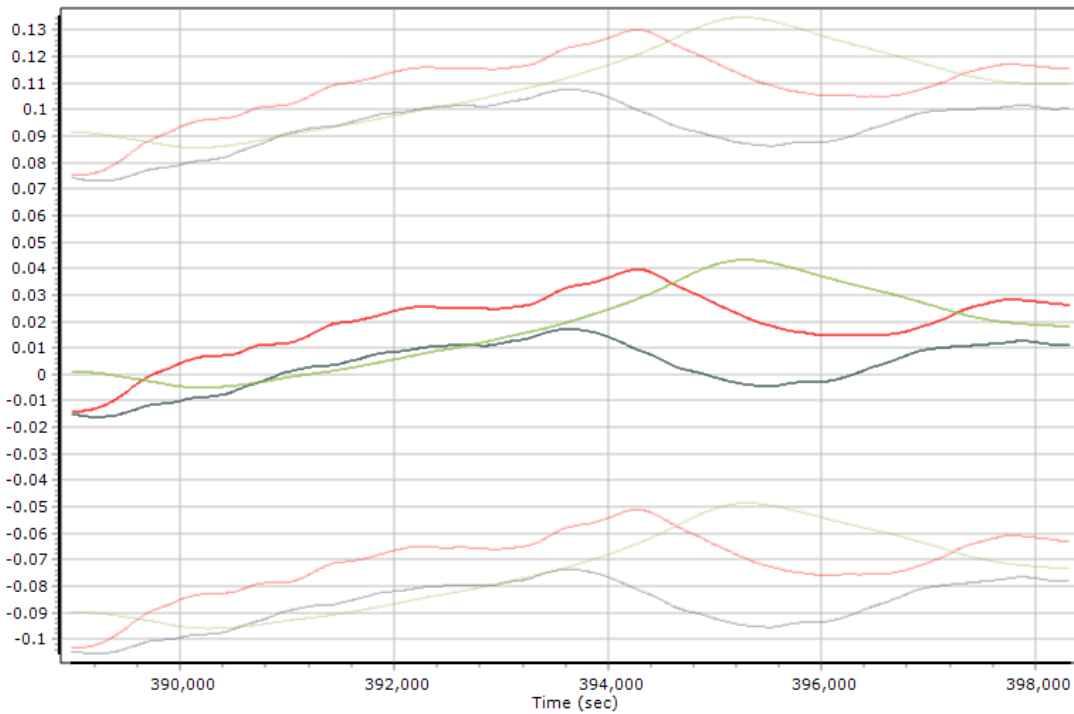


Sensor Errors

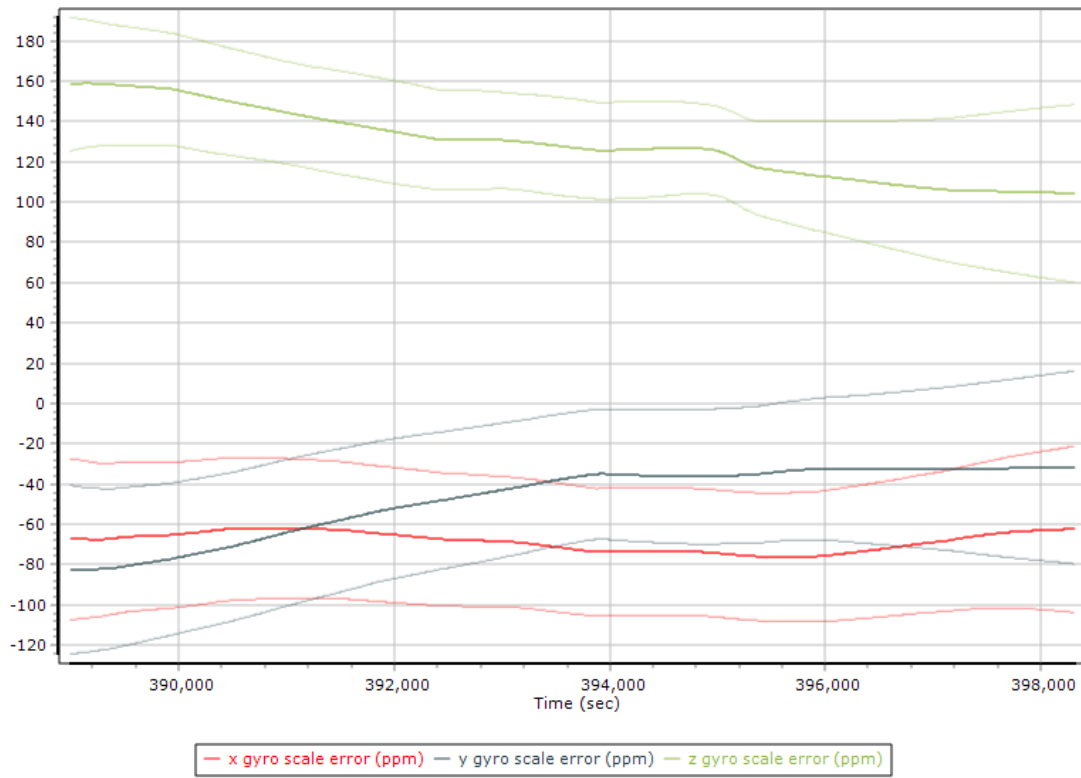




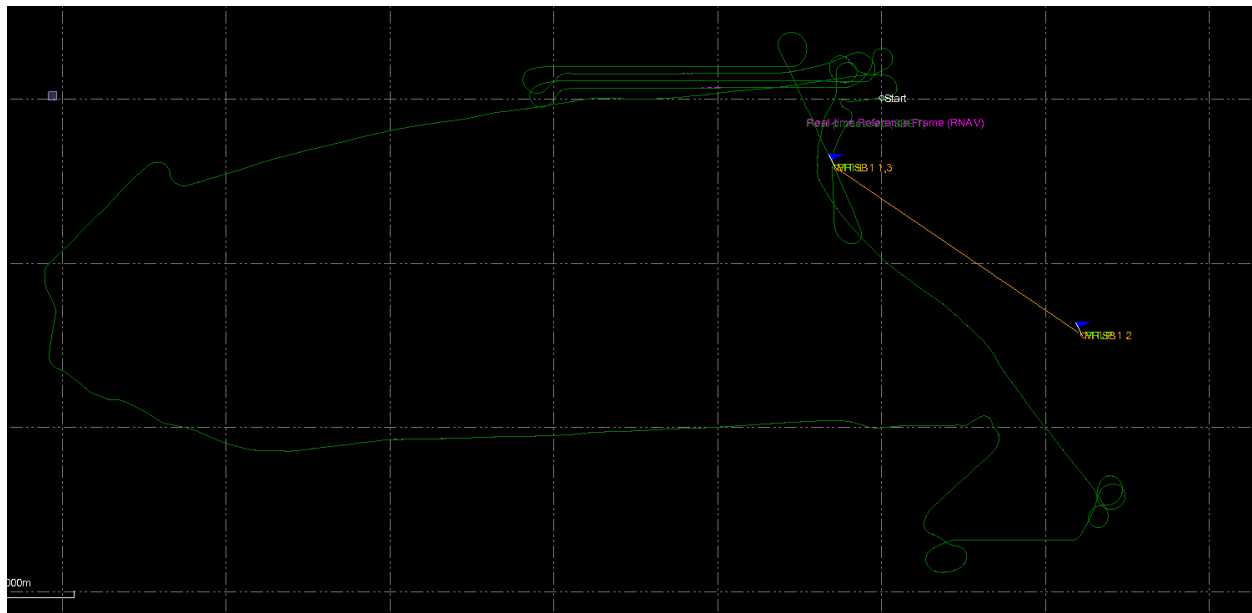
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



RBV18130B



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: -0.034 m
Y: -0.010 m
Z: -0.352 m

Stabilized Mount to IMU Mounting Angles

X: 0.000 deg
Y: 0.000 deg
Z: 0.000 deg

Stabilized Mount to Primary GNSS Lever Arm

X: -0.037 m
Y: 0.007 m
Z: -0.985 m

Aircraft to Stabilized Mount Mounting Angles

X: 0.000 deg
Y: 0.000 deg
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

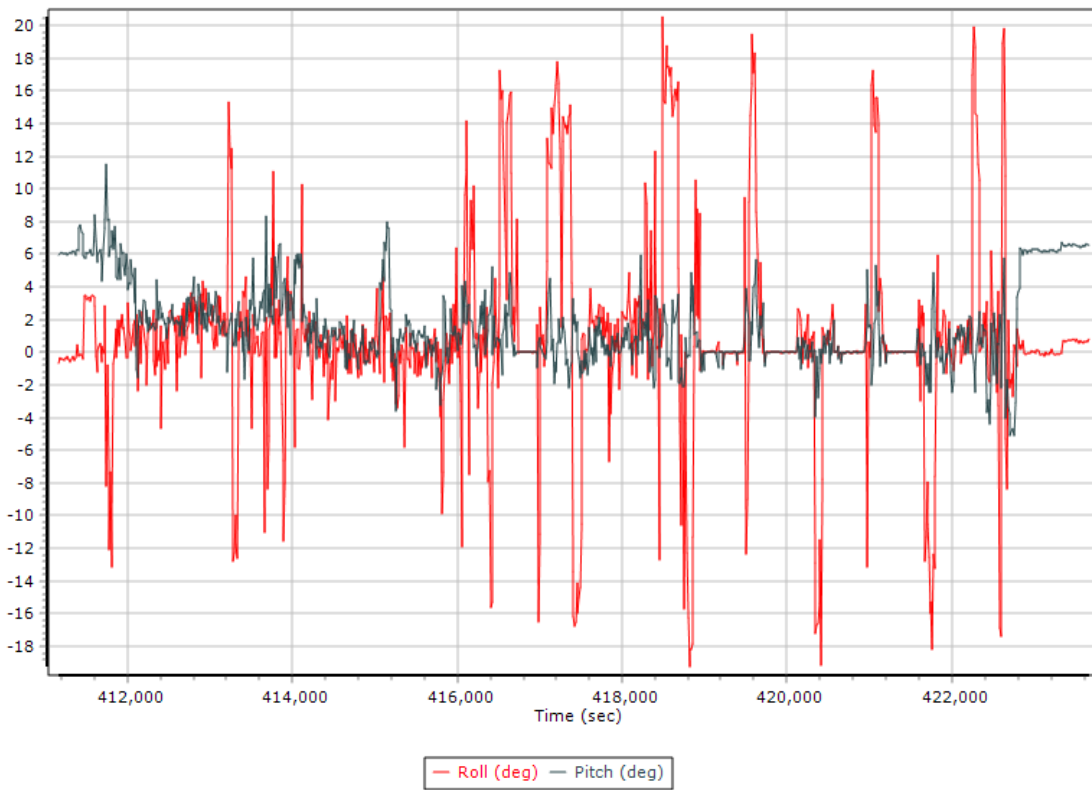
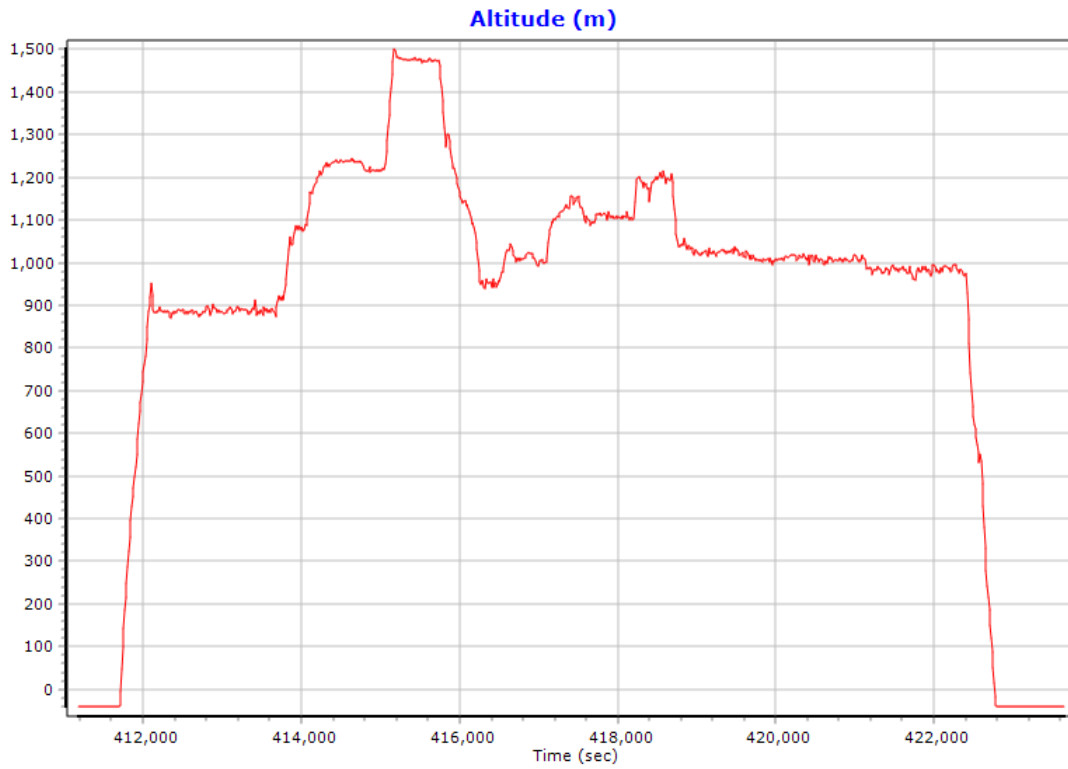
Start: 411163.000
End: 423665.000

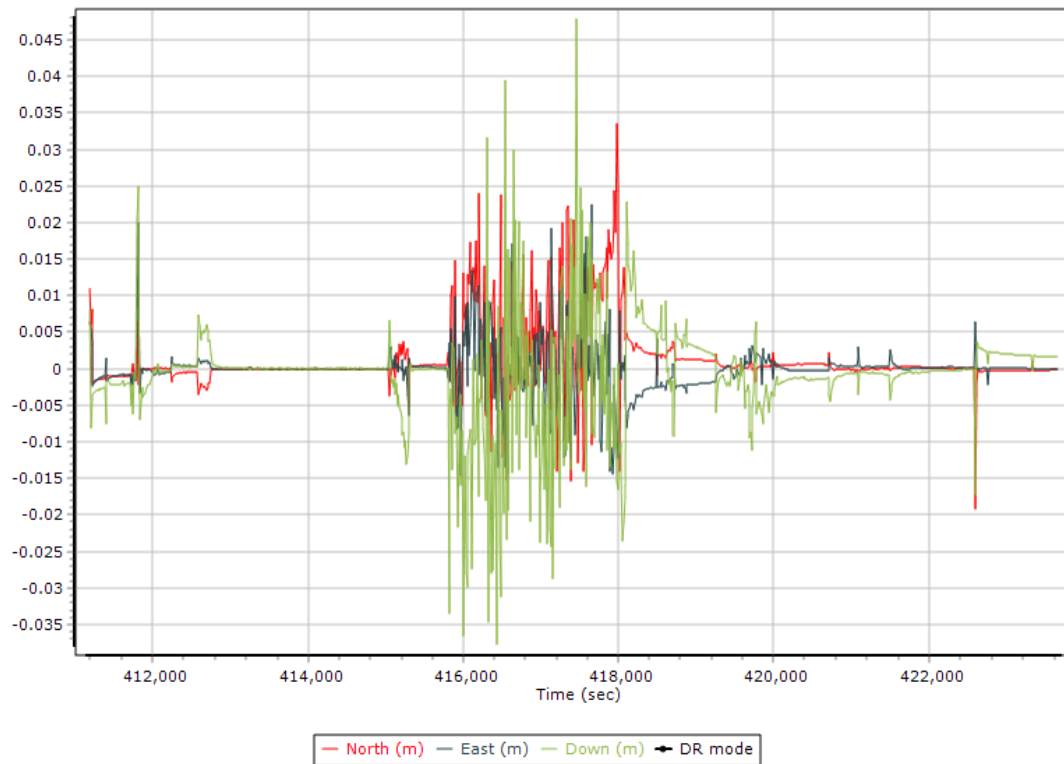
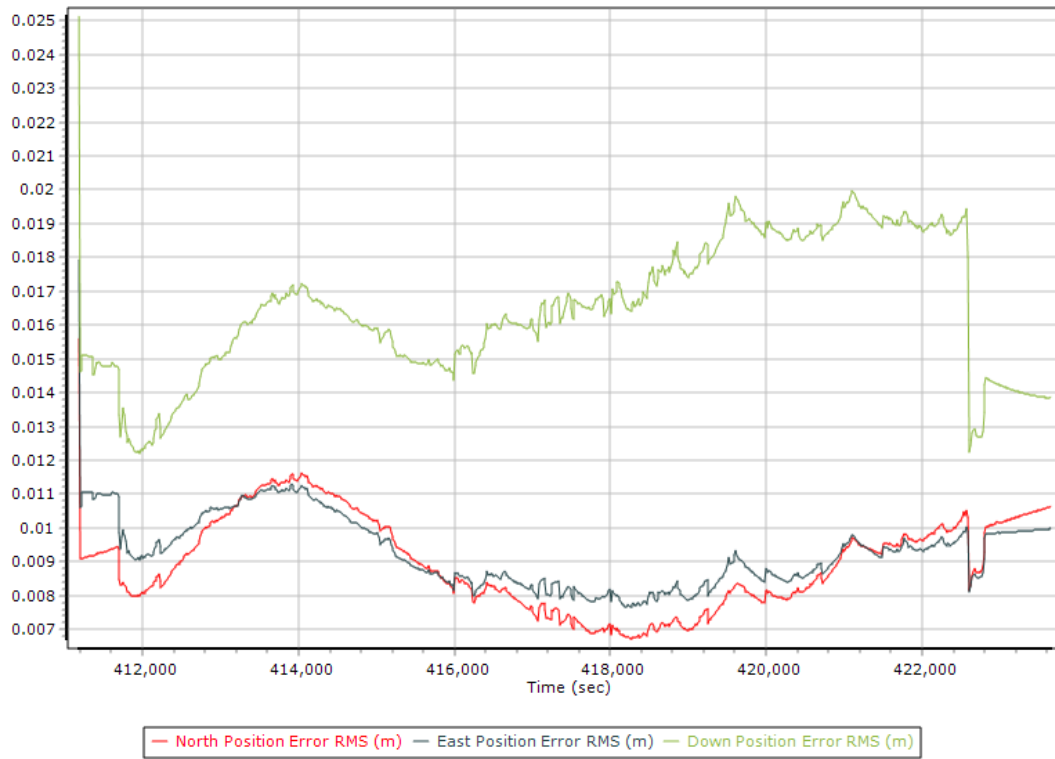
Entire time interval
 Seconds of start week

UTC Offset: 18.000

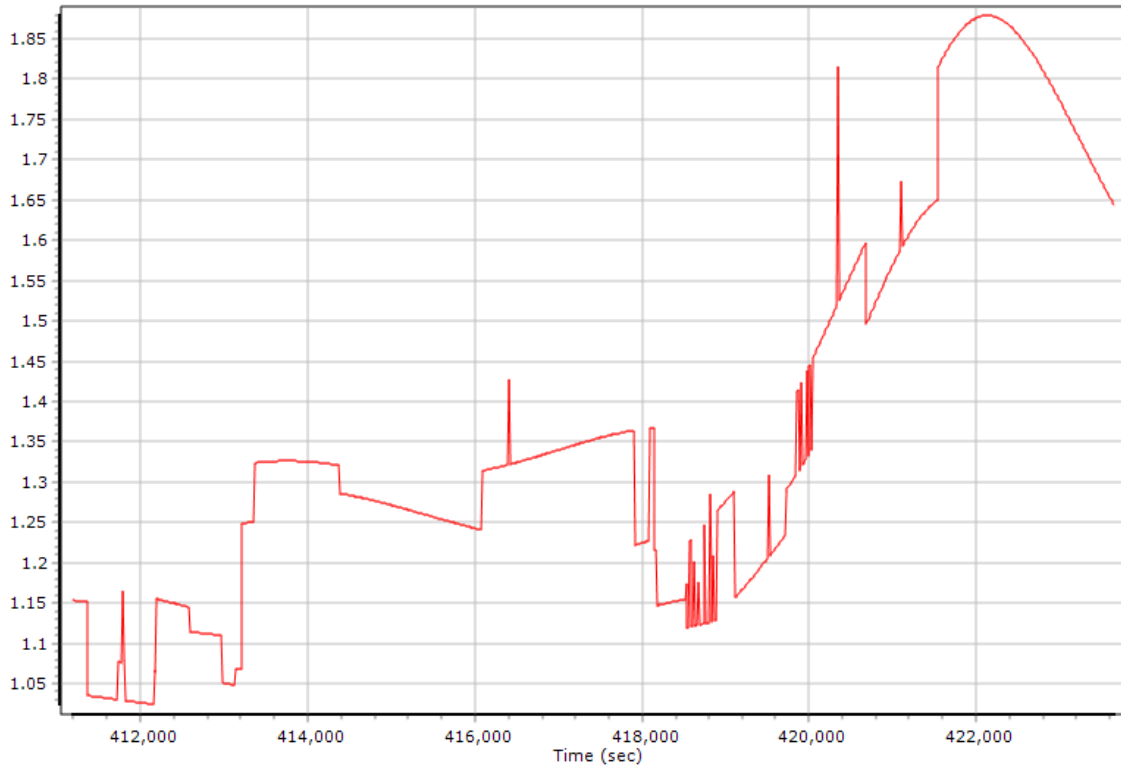
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel

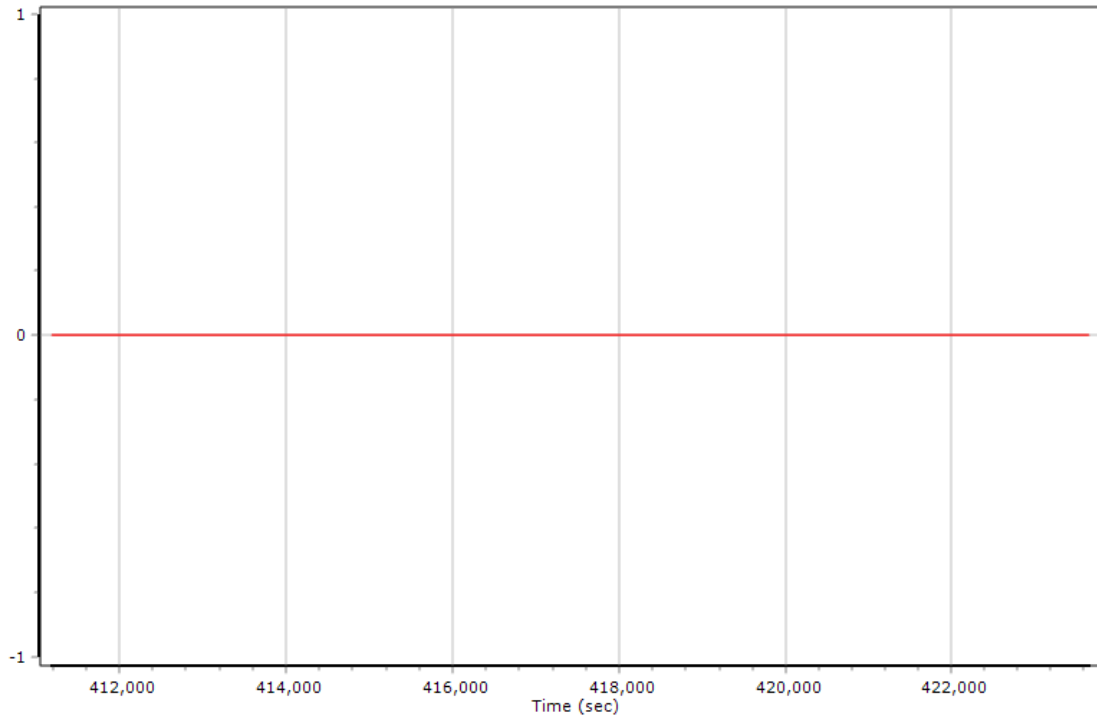




PDOP

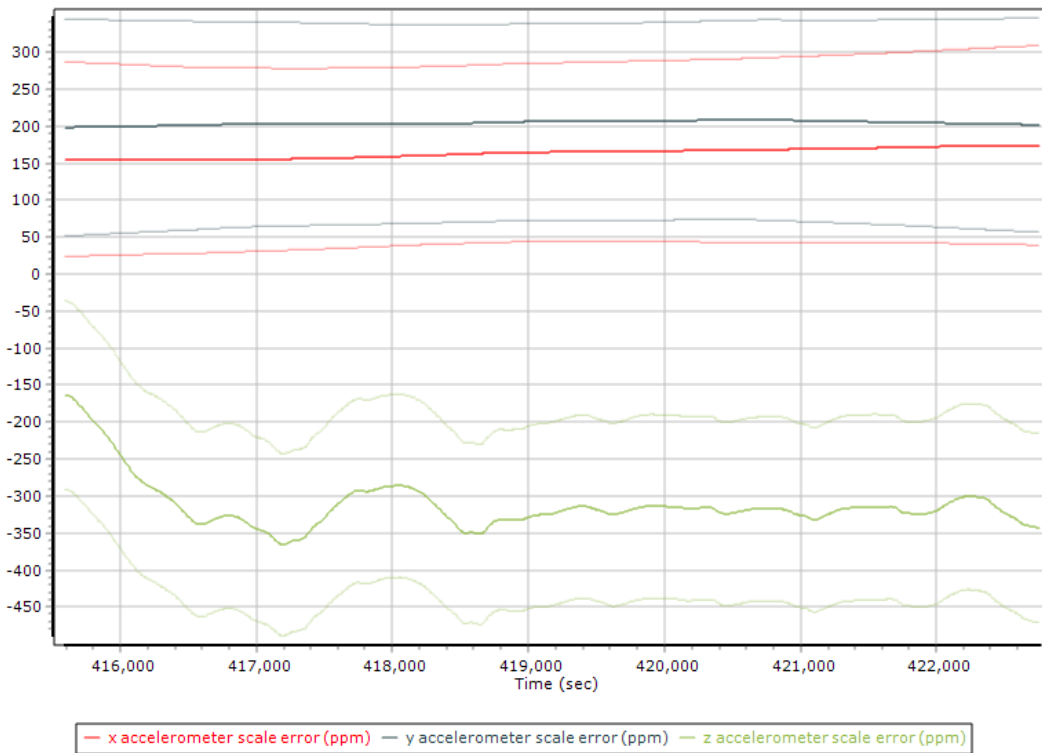
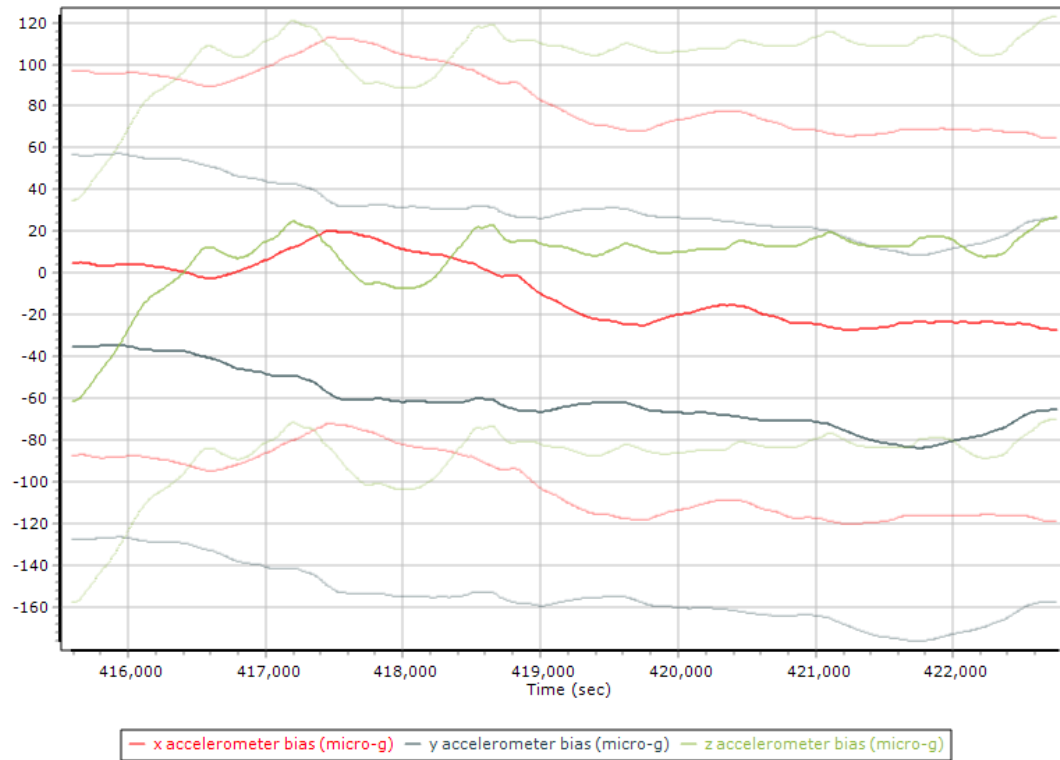


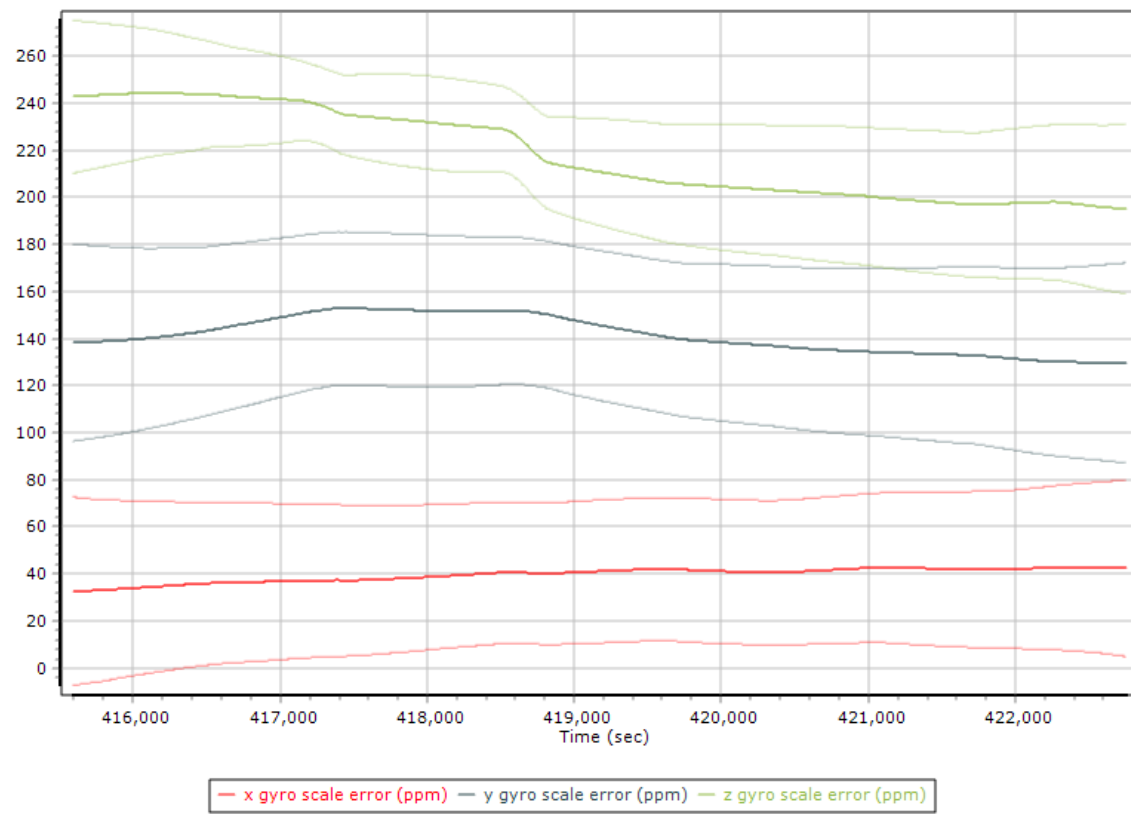
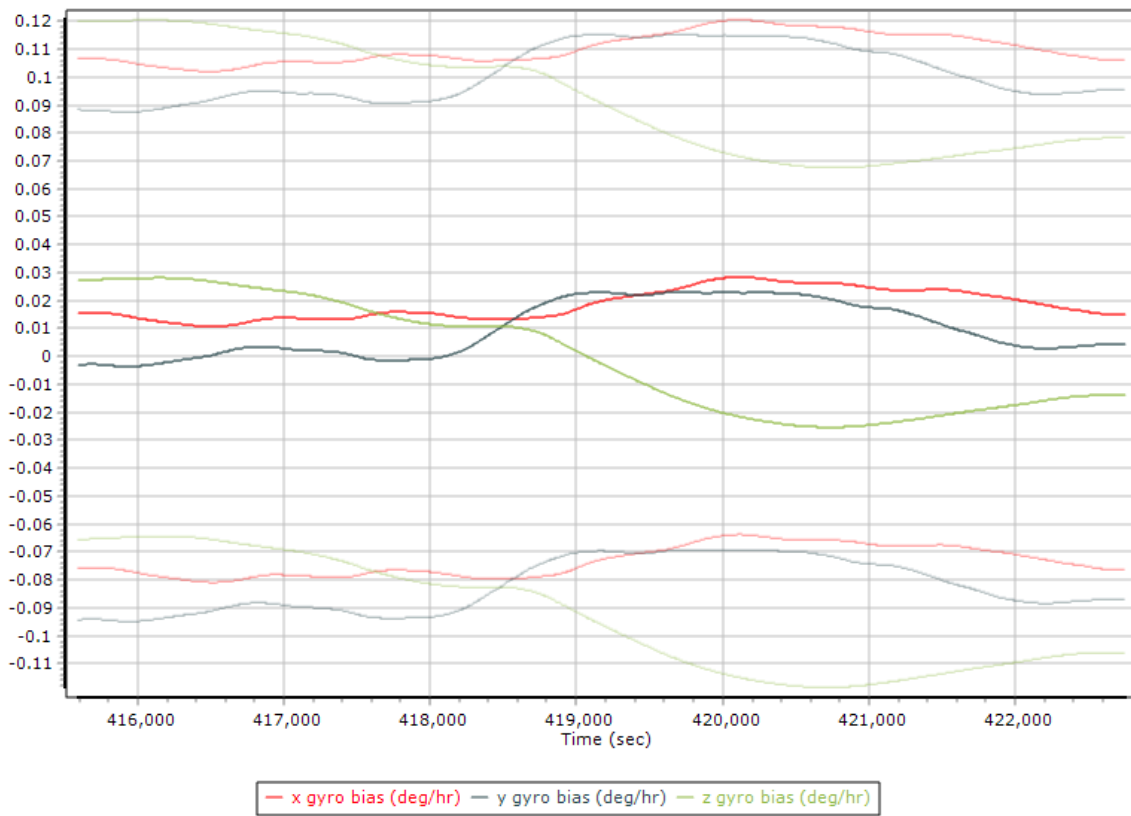
Processing mode



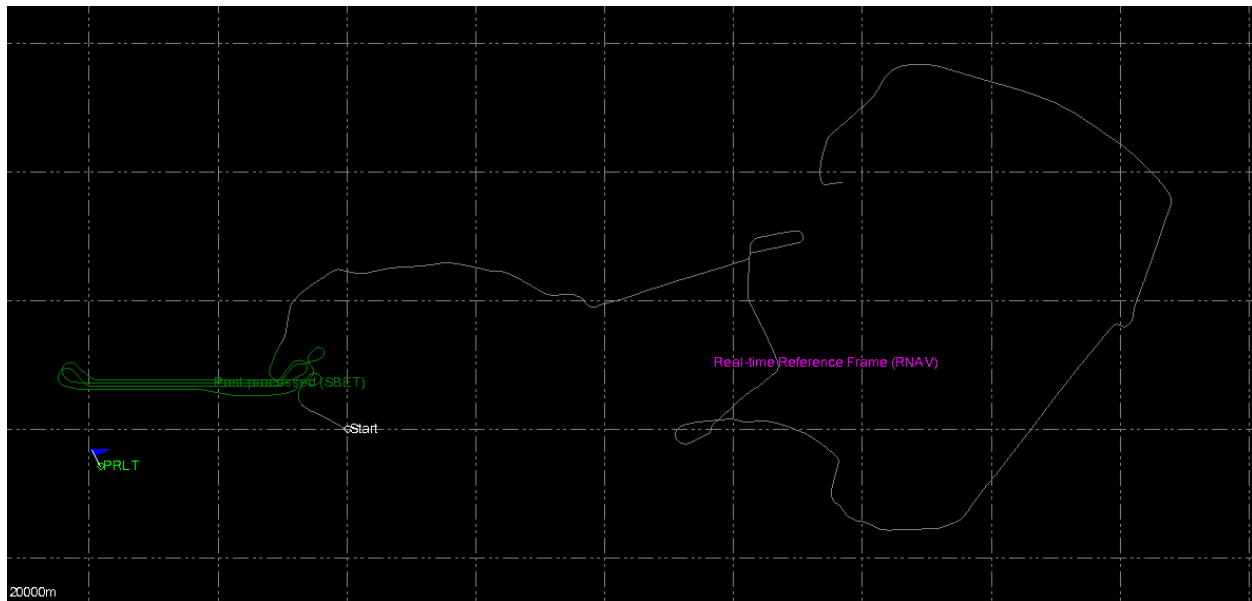
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





RBV18131A



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
Arm X: -0.037 m	X: 0.000 deg
Y: 0.007 m	Y: 0.000 deg
Z: -0.985 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

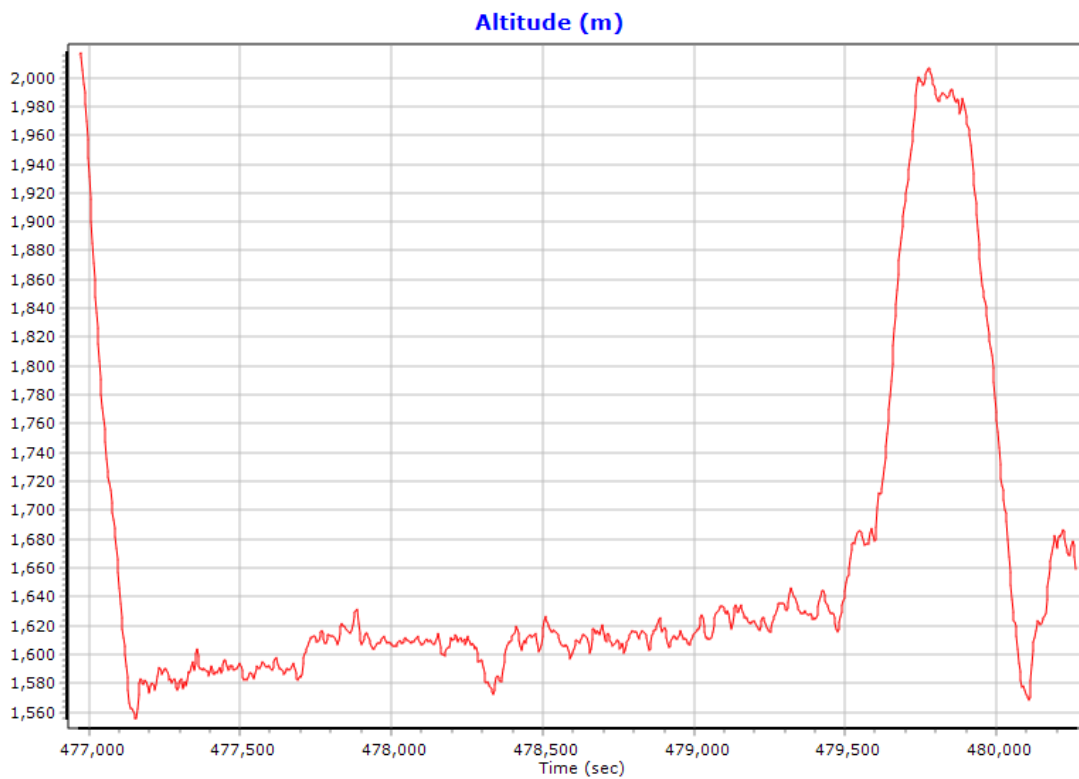
Timing

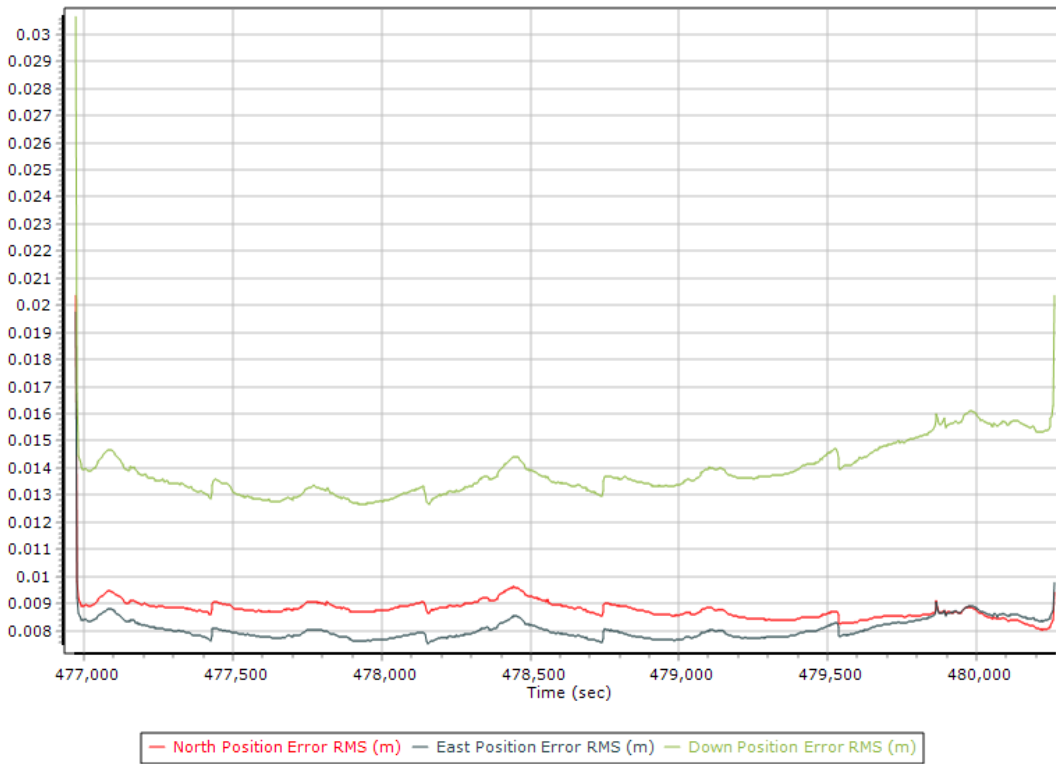
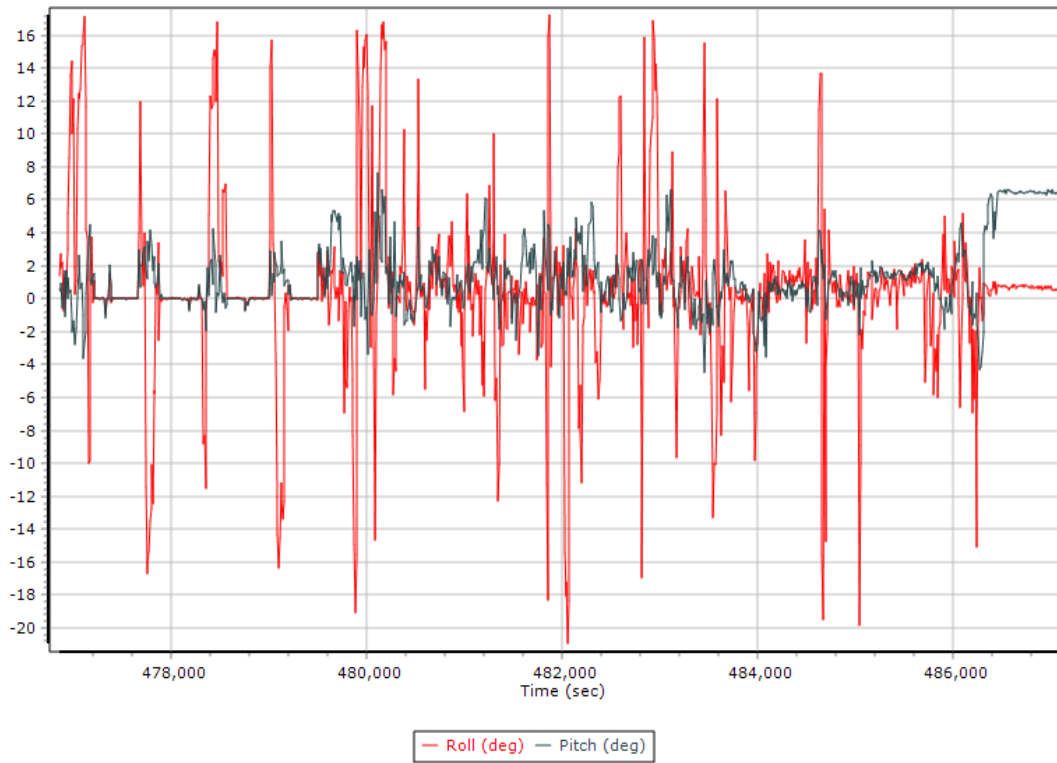
Start: 476967.837
End: 480266.611
UTC Offset: 18.000

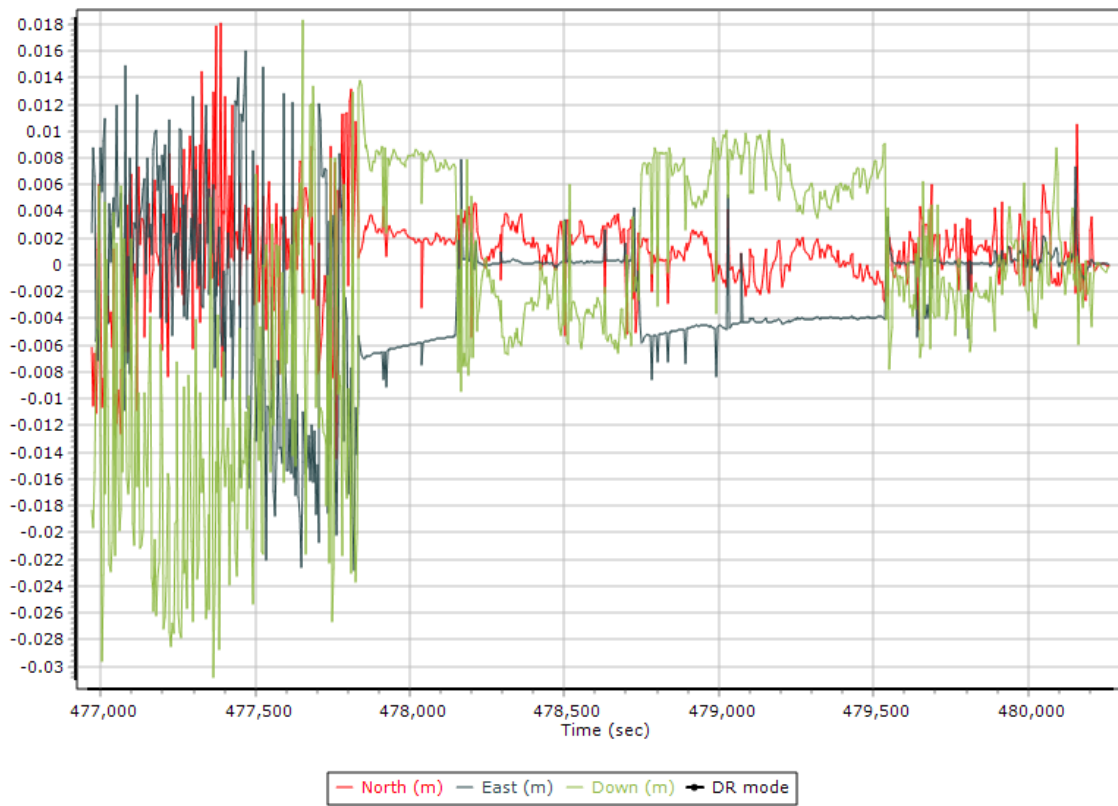
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

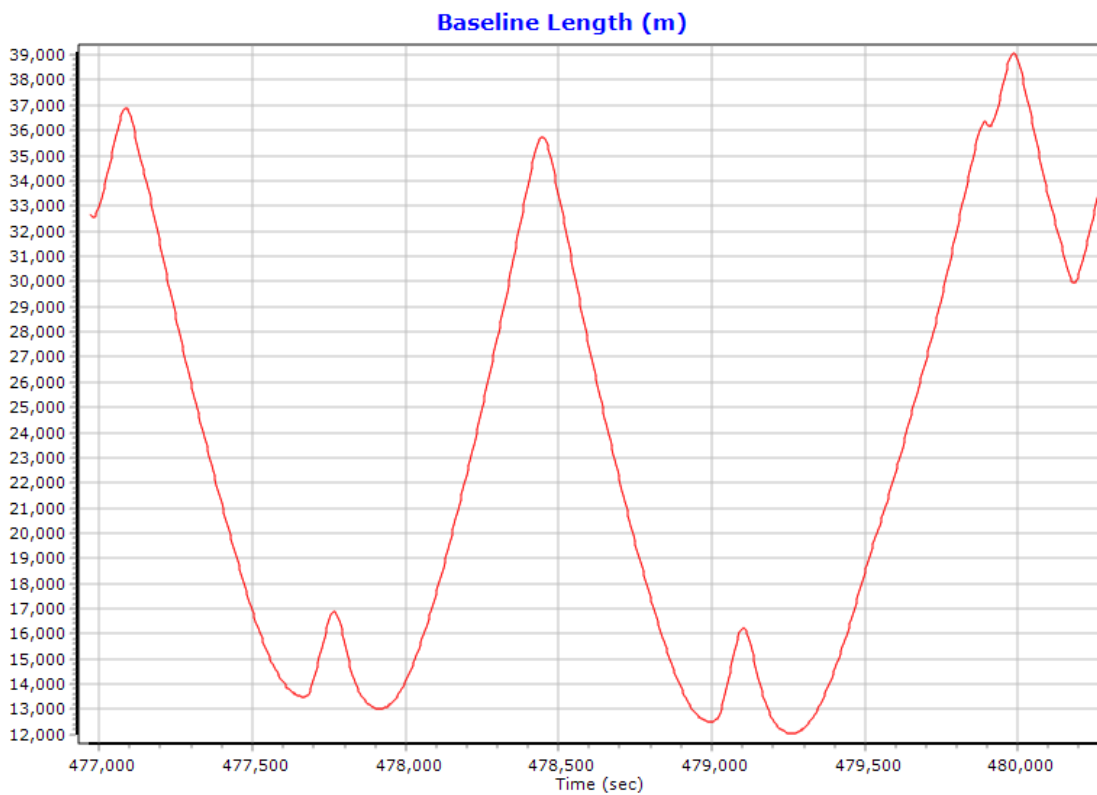
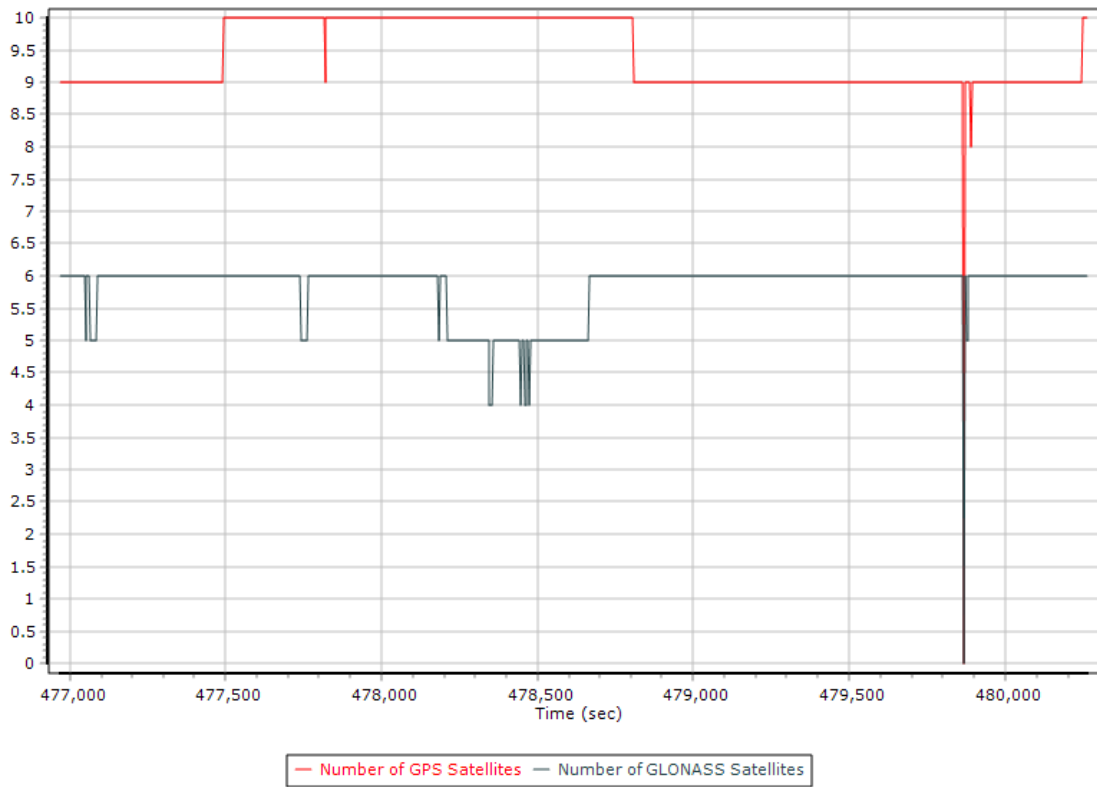
Entire time interval:
Seconds of start week:

OK Cancel

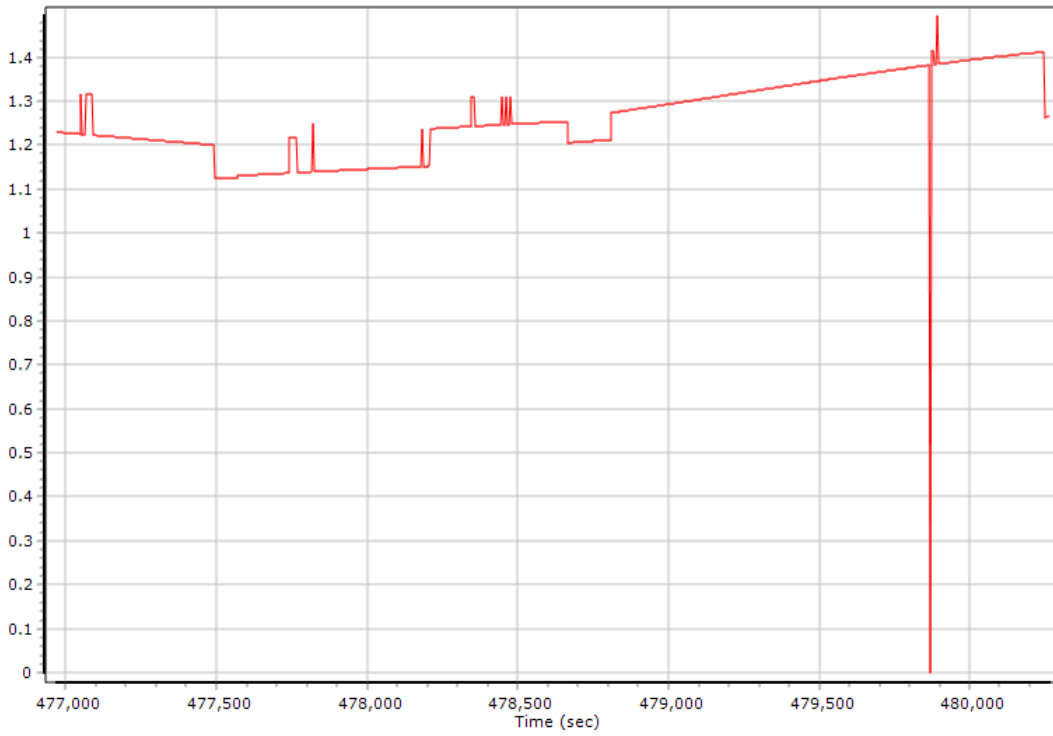




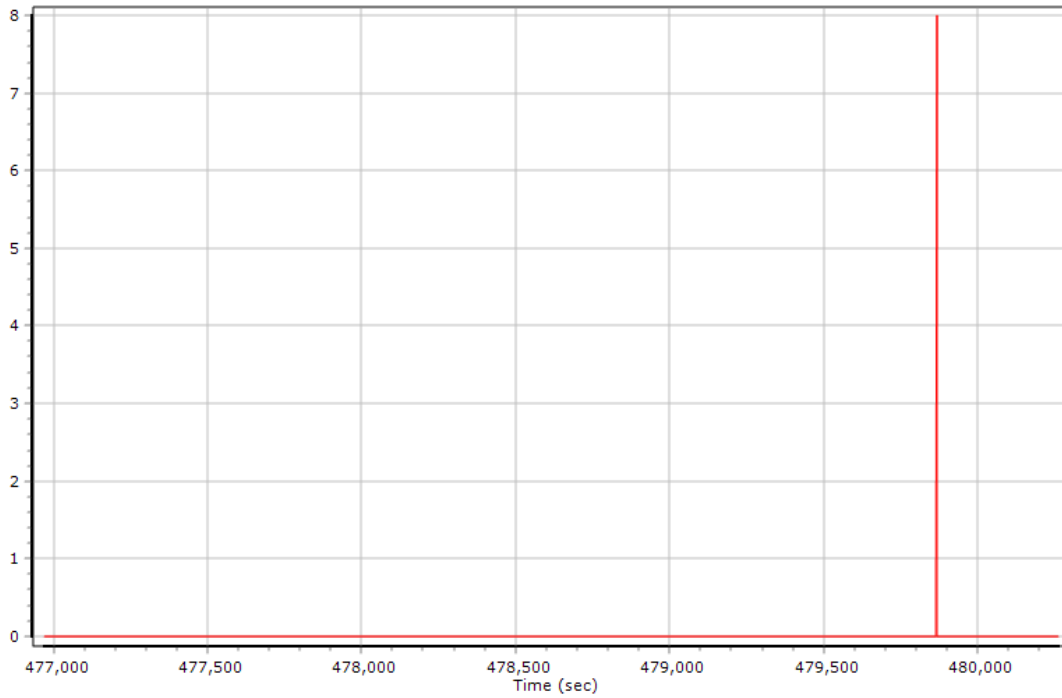




PDOP

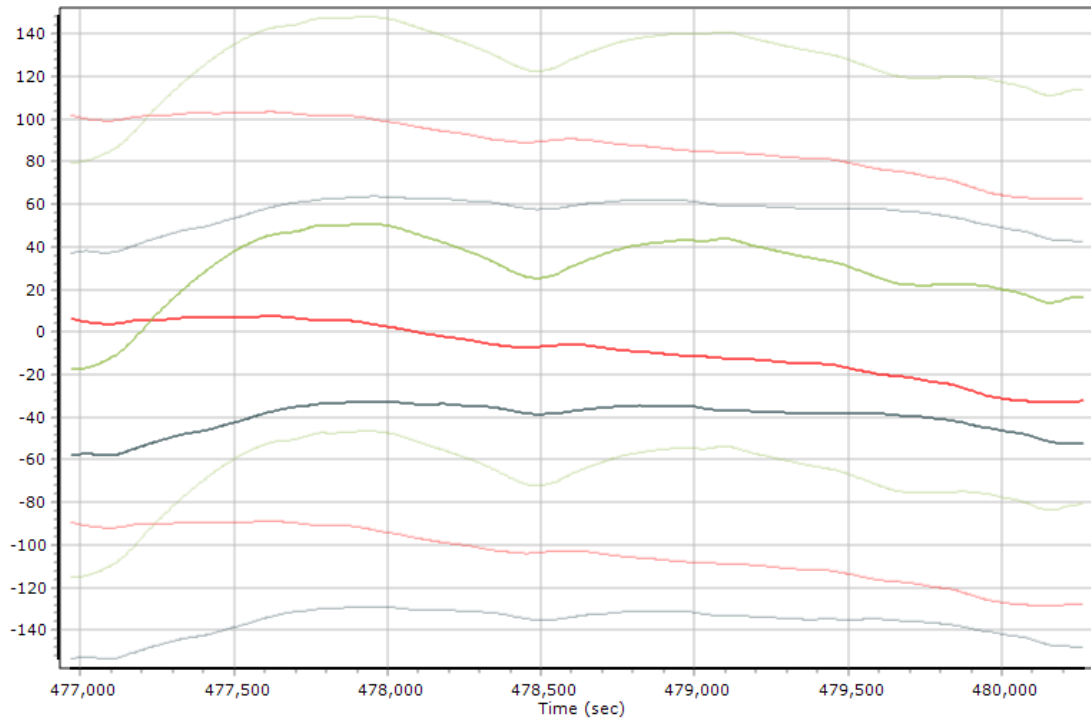


Processing mode

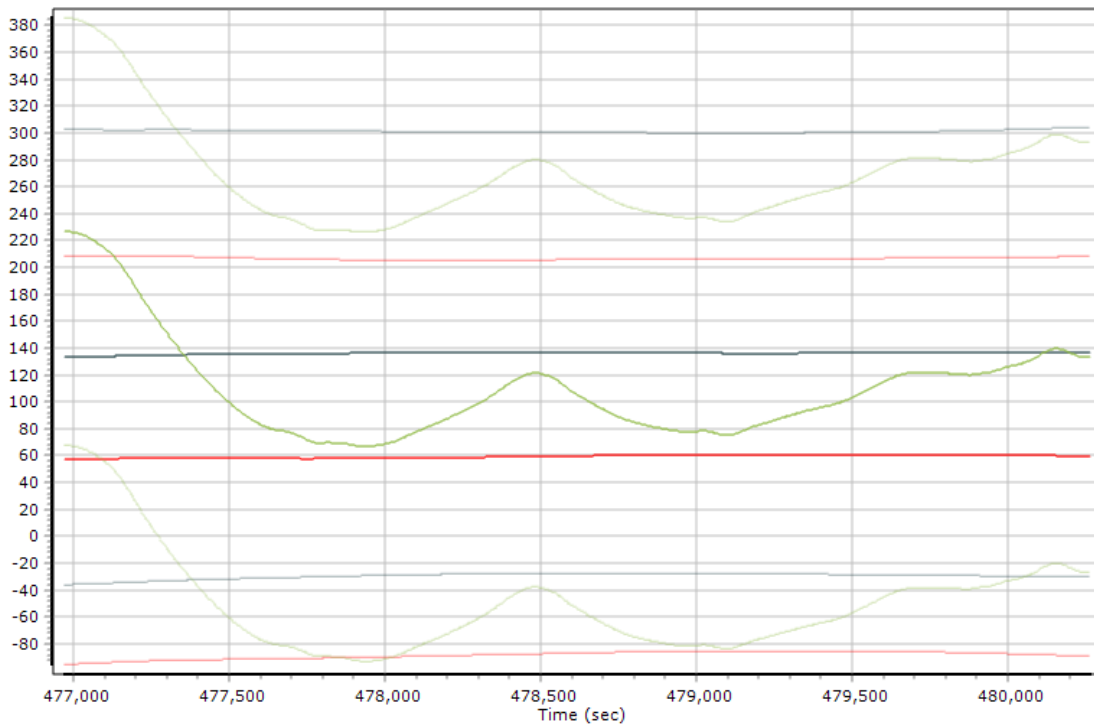


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

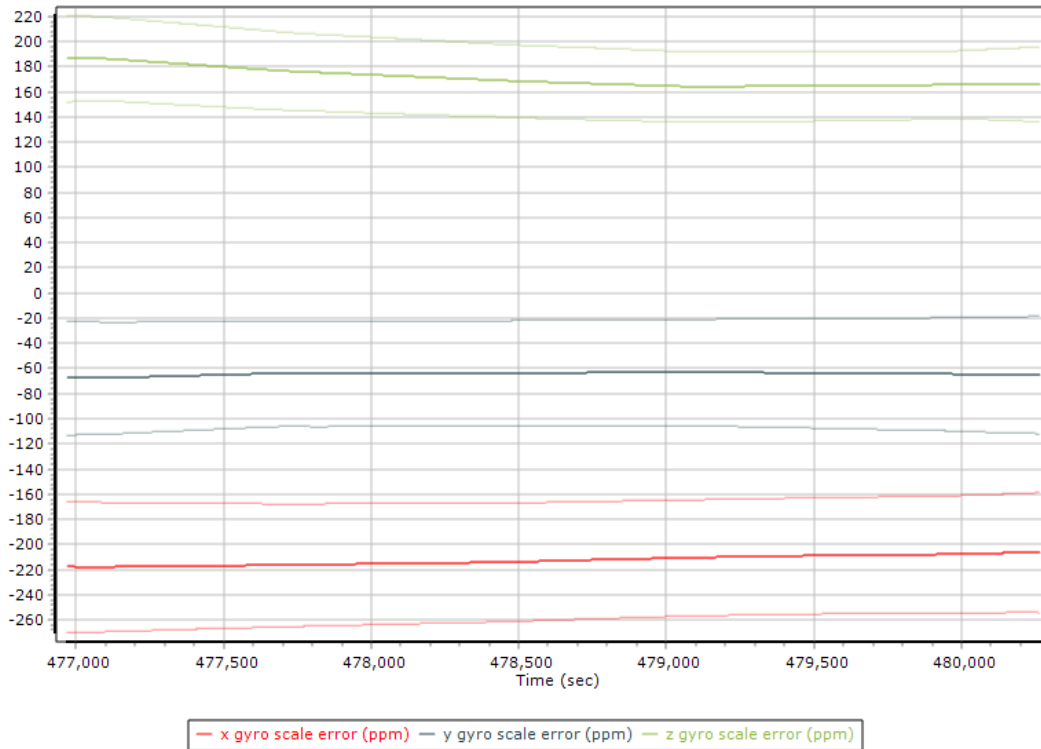
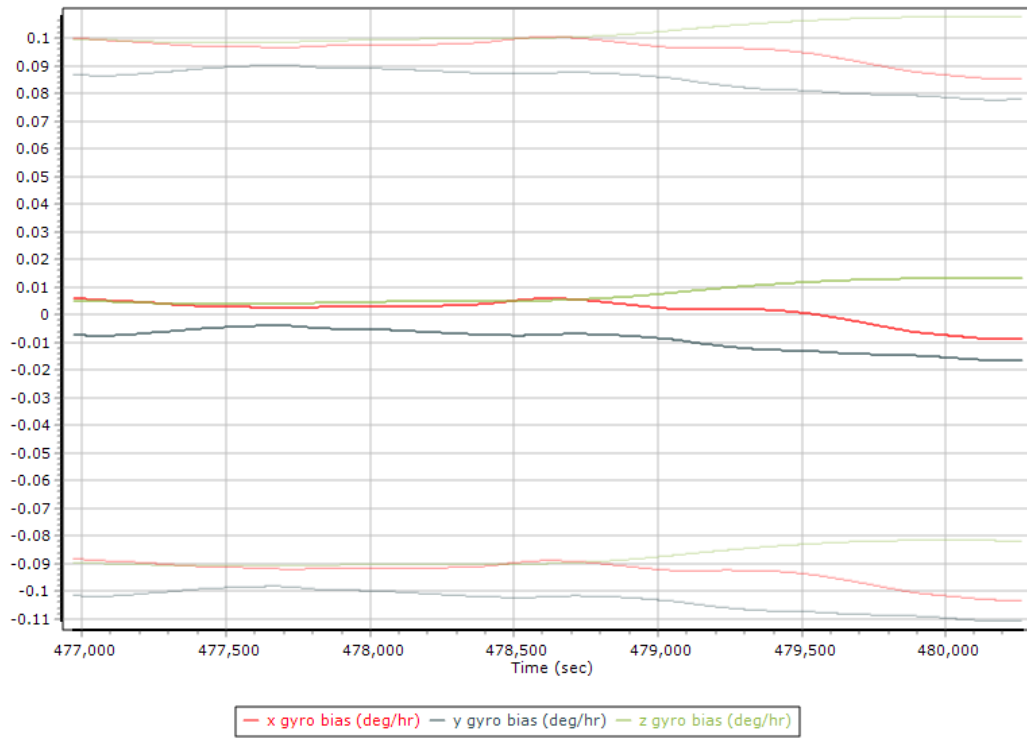
Sensor Errors



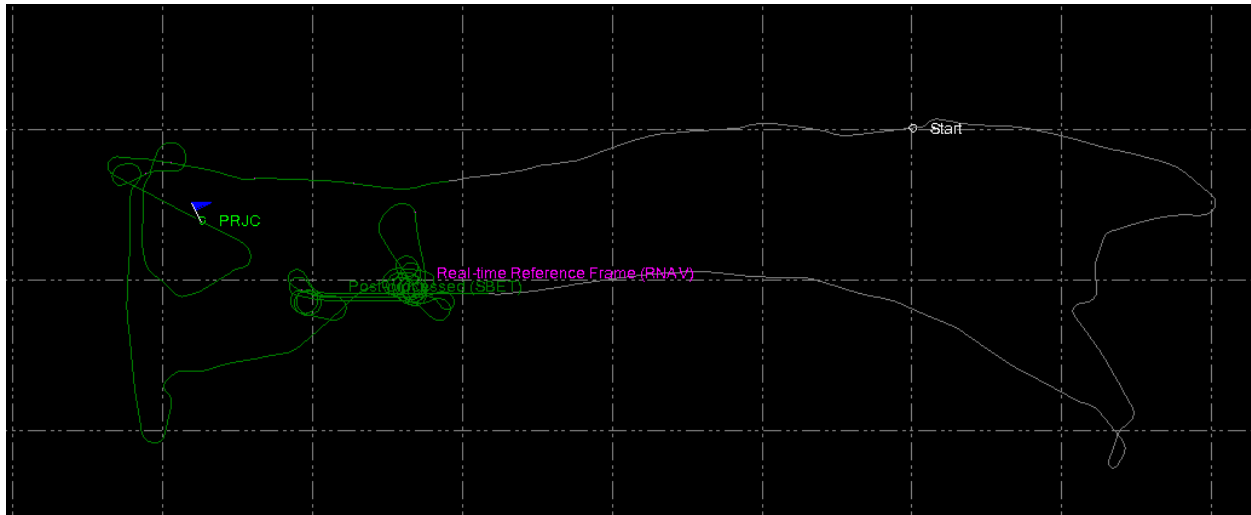
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



RBV18136A



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

Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.037 m	0.007 m	-0.985 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	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

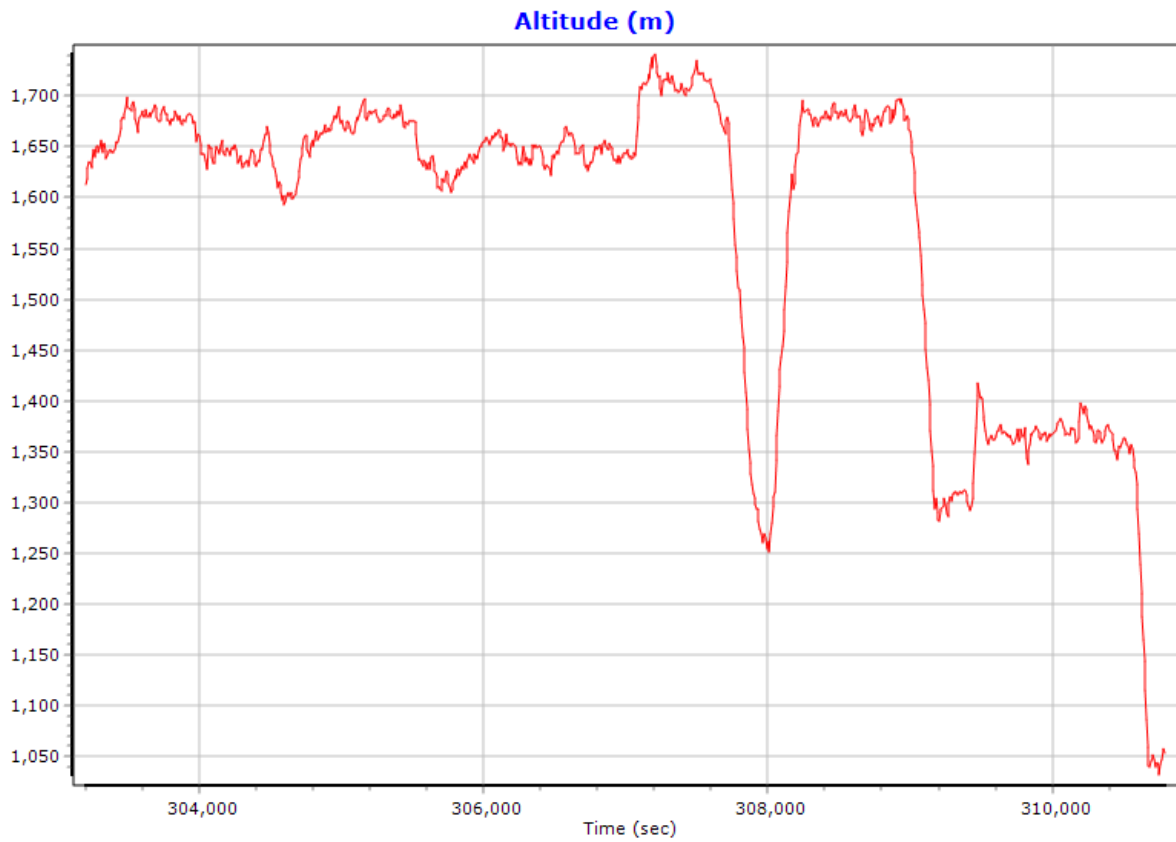
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
Timing
Algorithms
Initialization
Lever Arms and Mounting Angles
Export
Camera
LiDAR
SAR

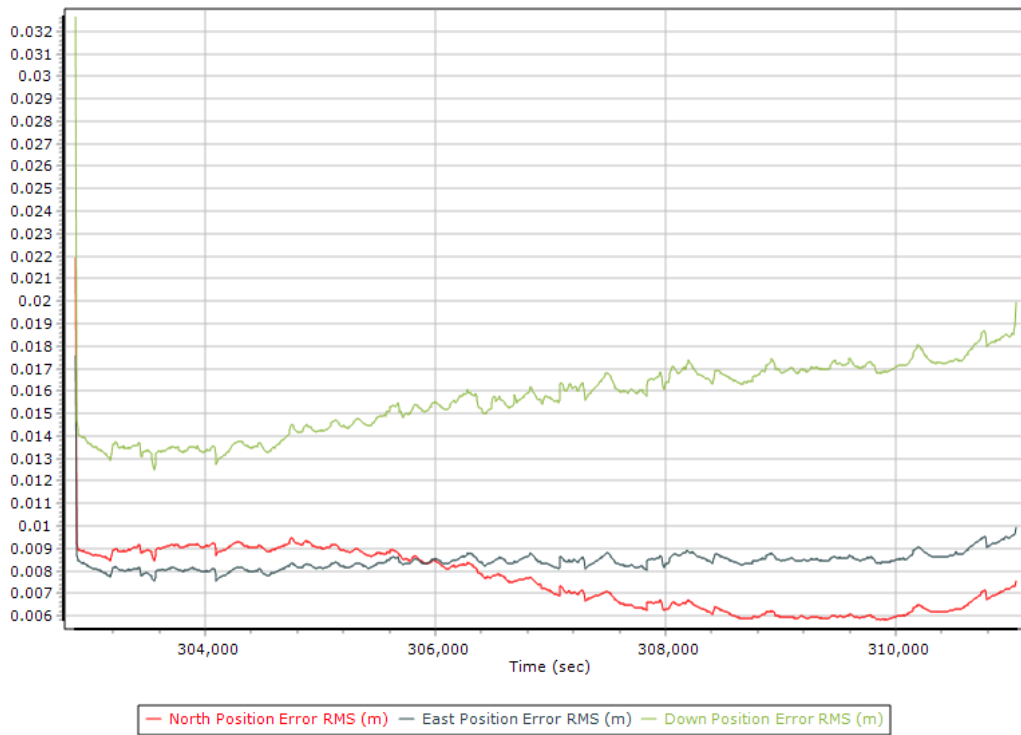
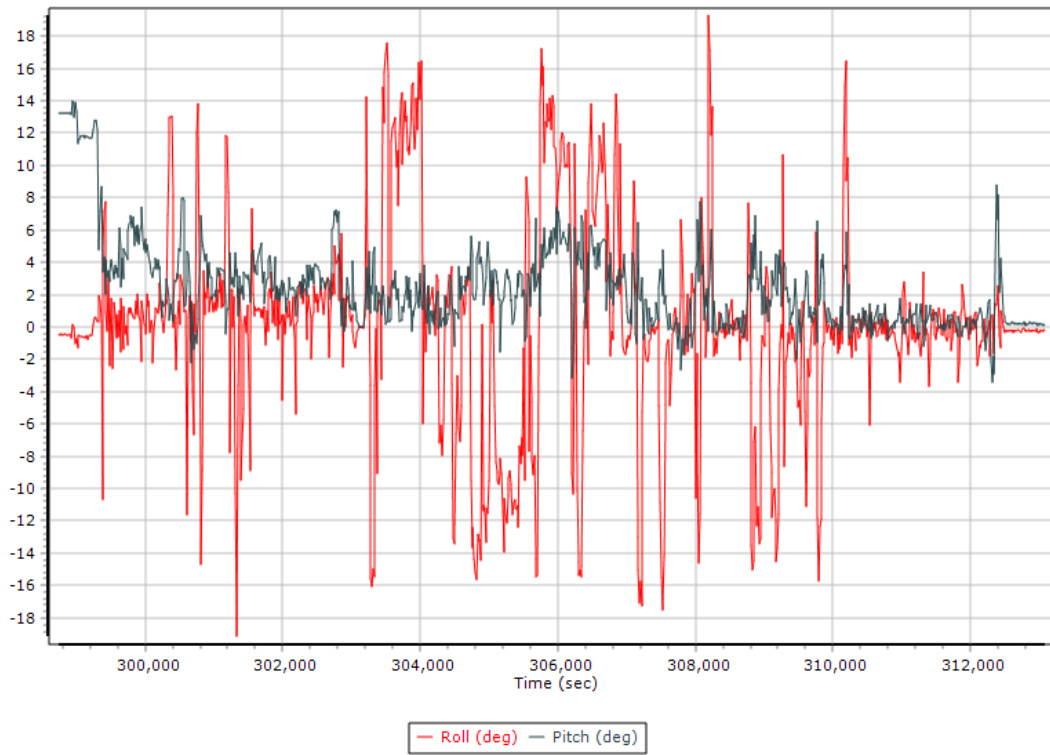
Timing

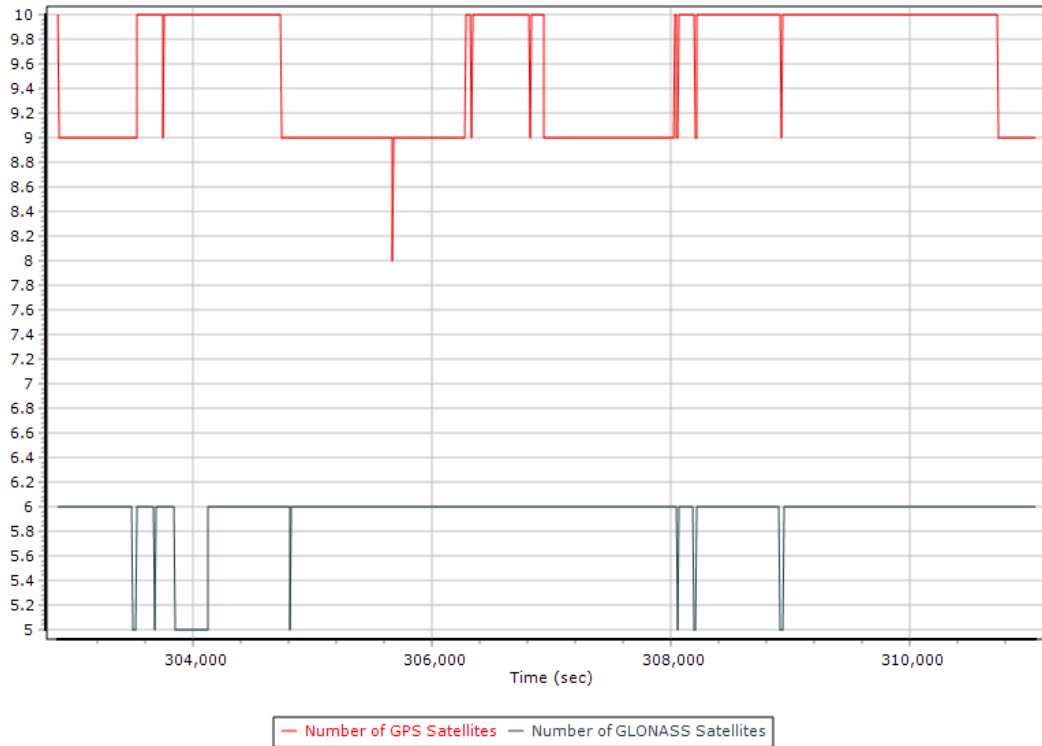
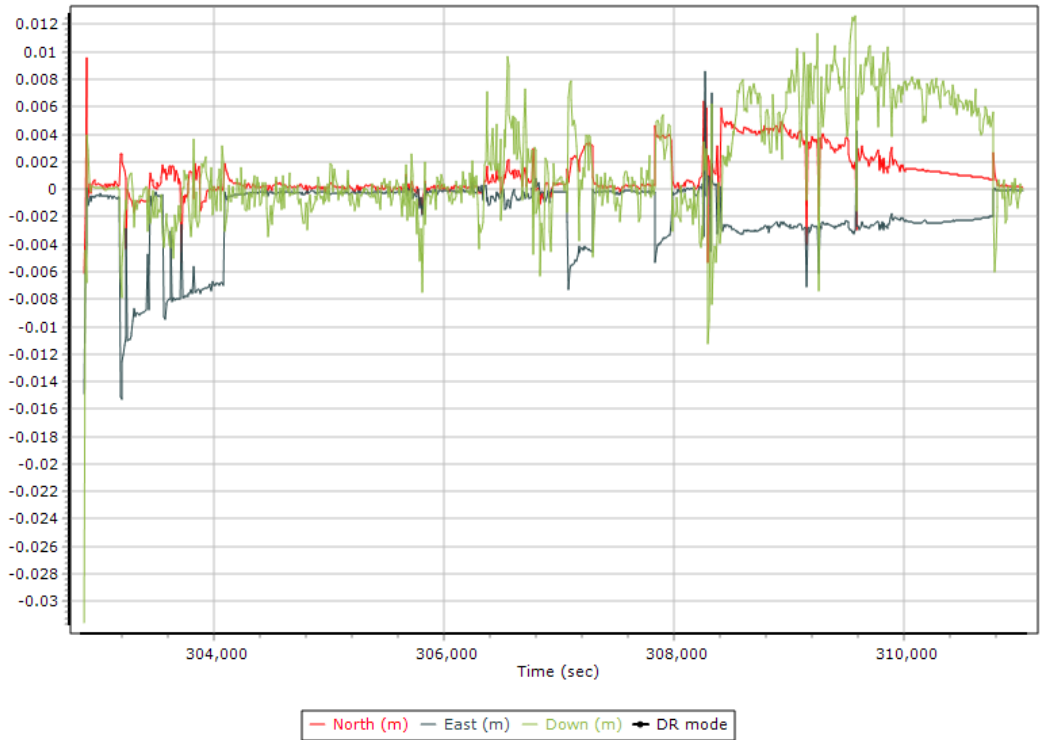
Start: 302871.274
End: 311053.194
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

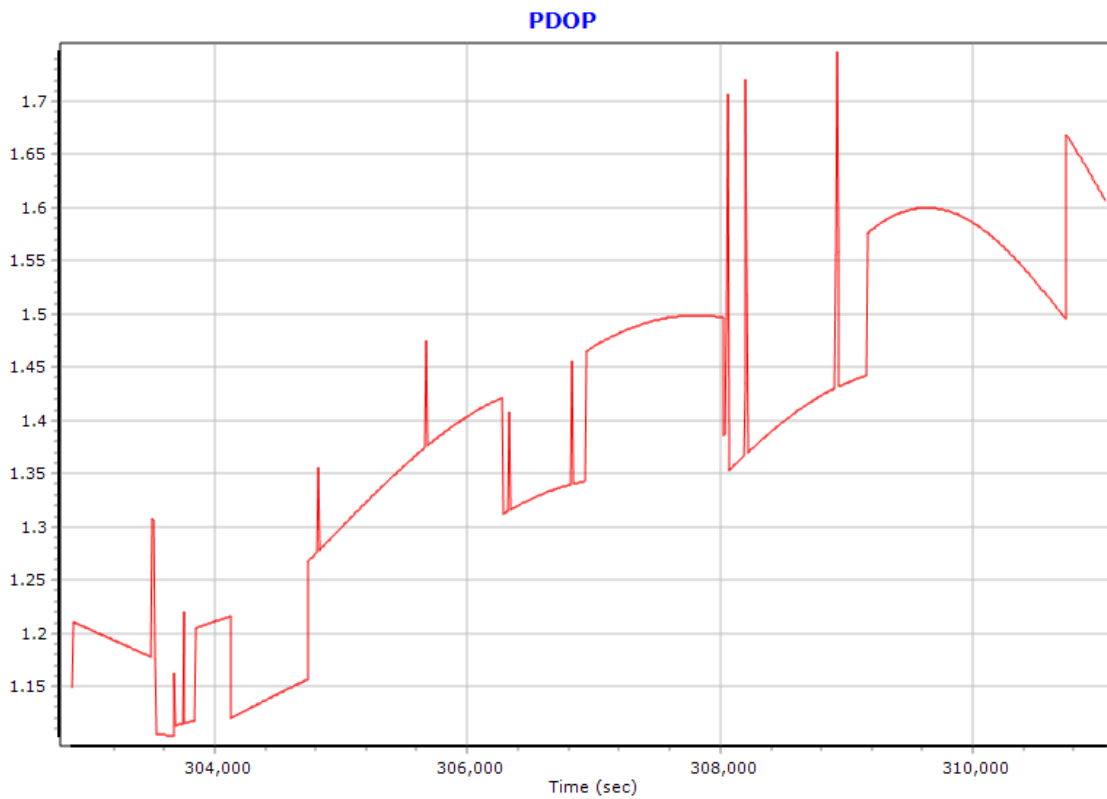
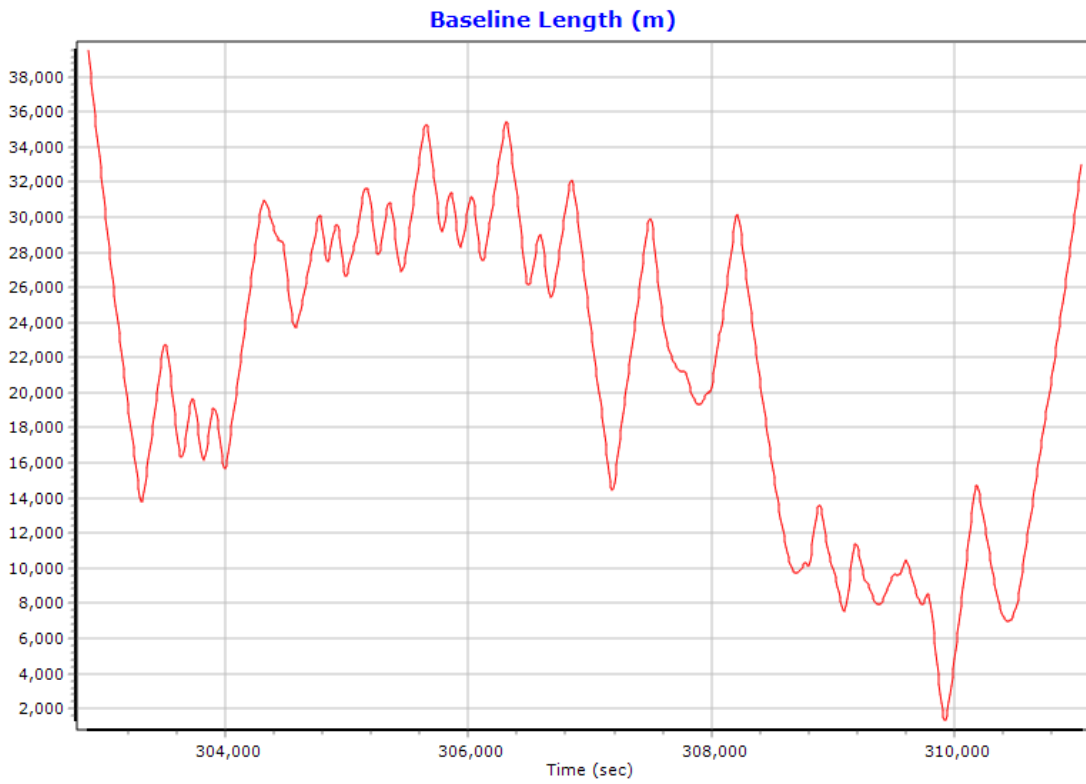
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

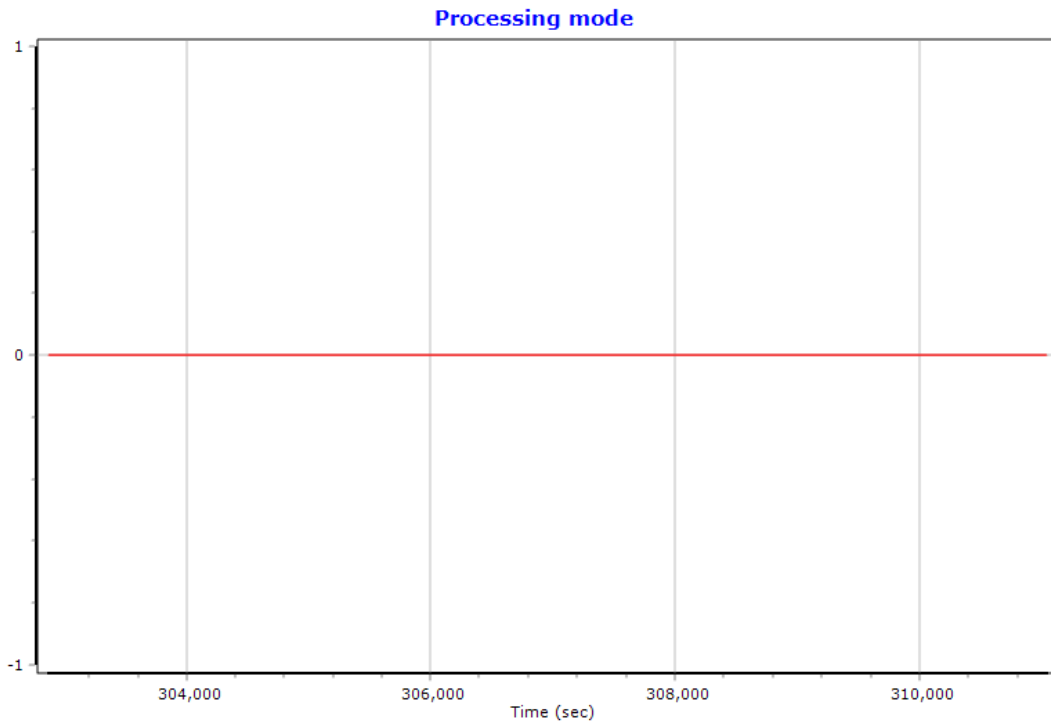
OK Cancel





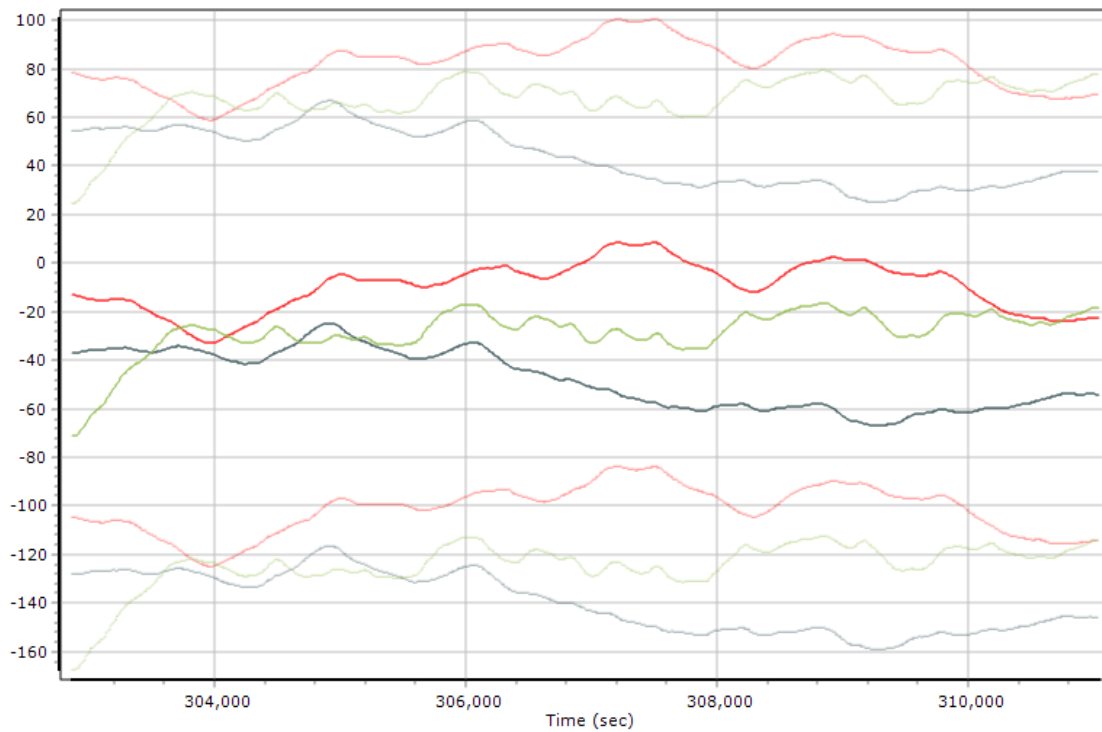




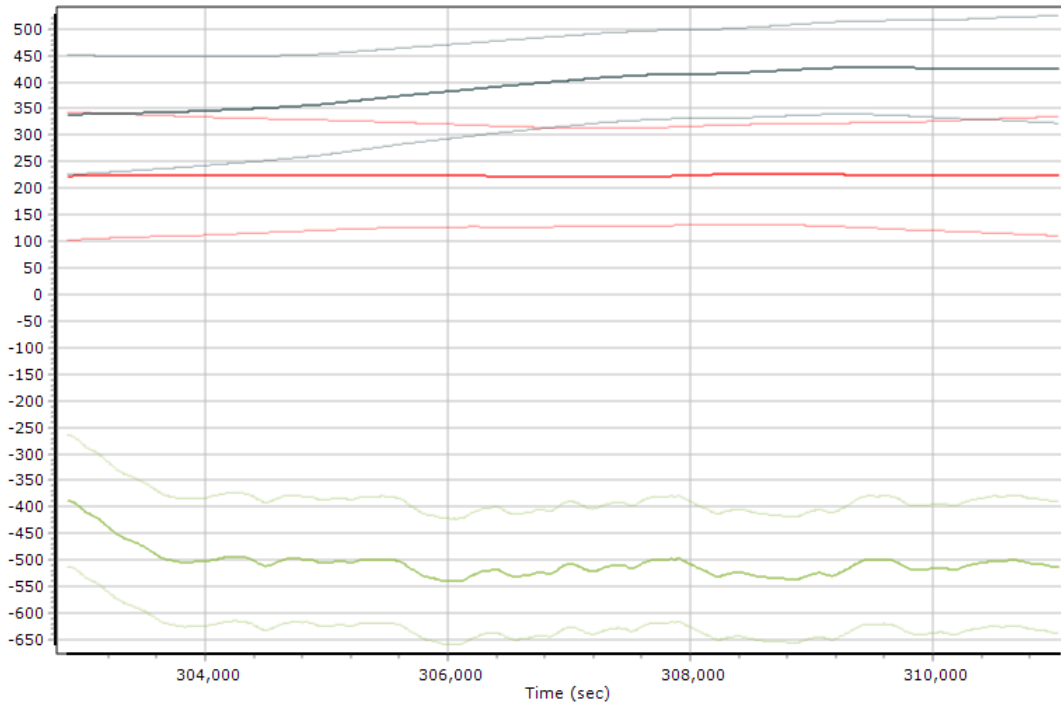


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

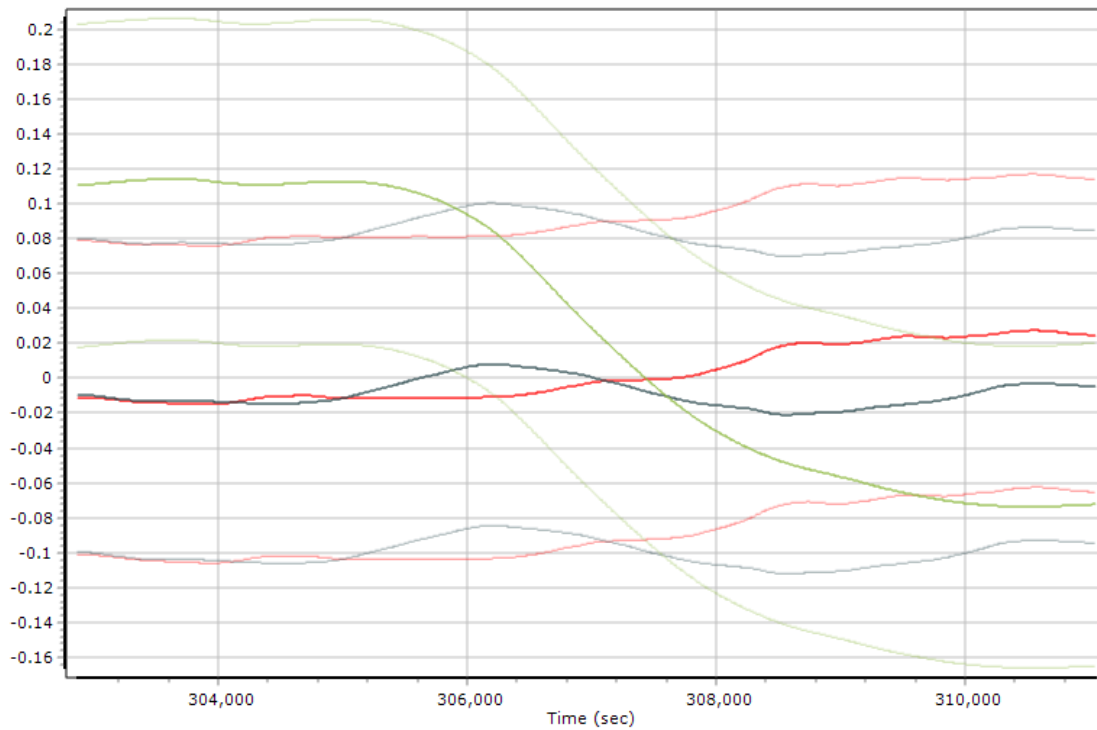
Sensor Errors



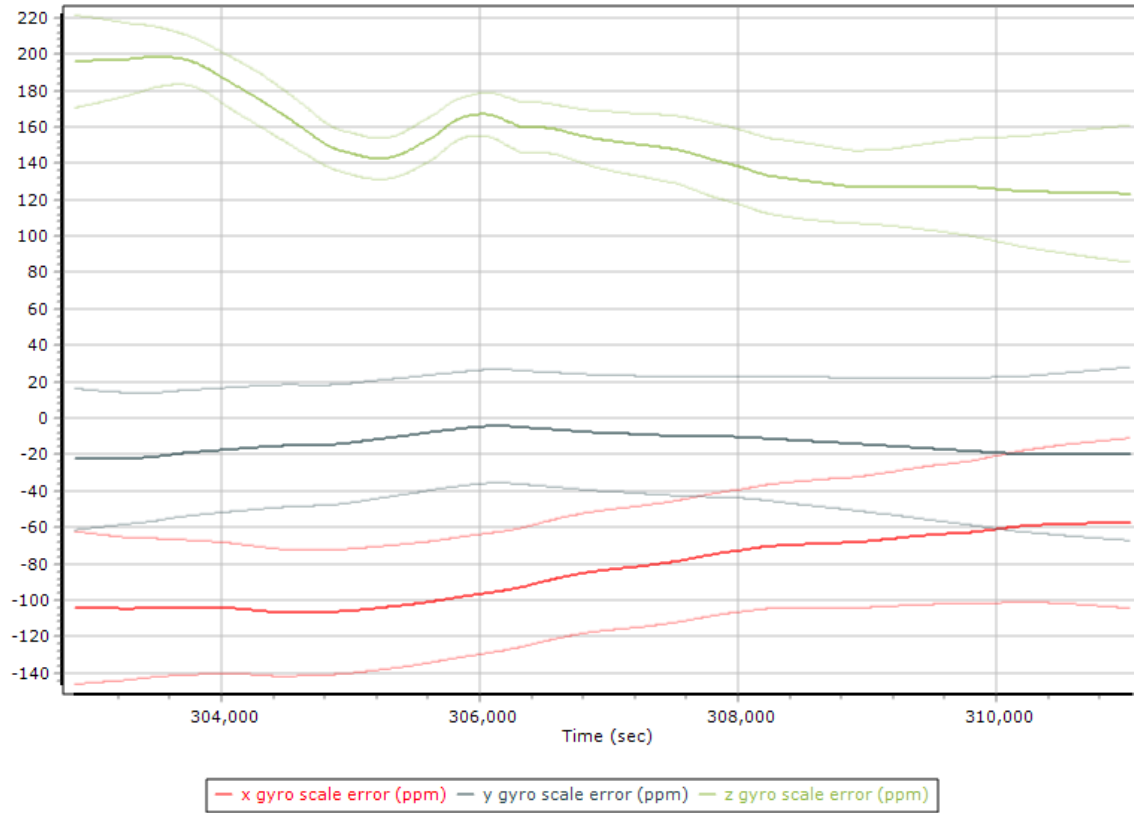
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



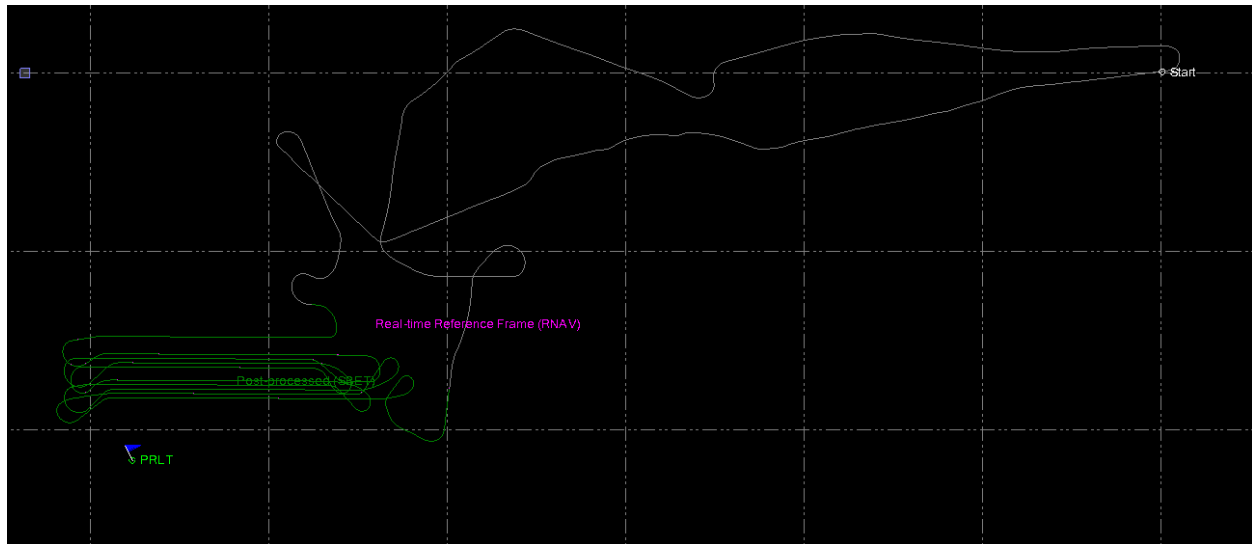
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

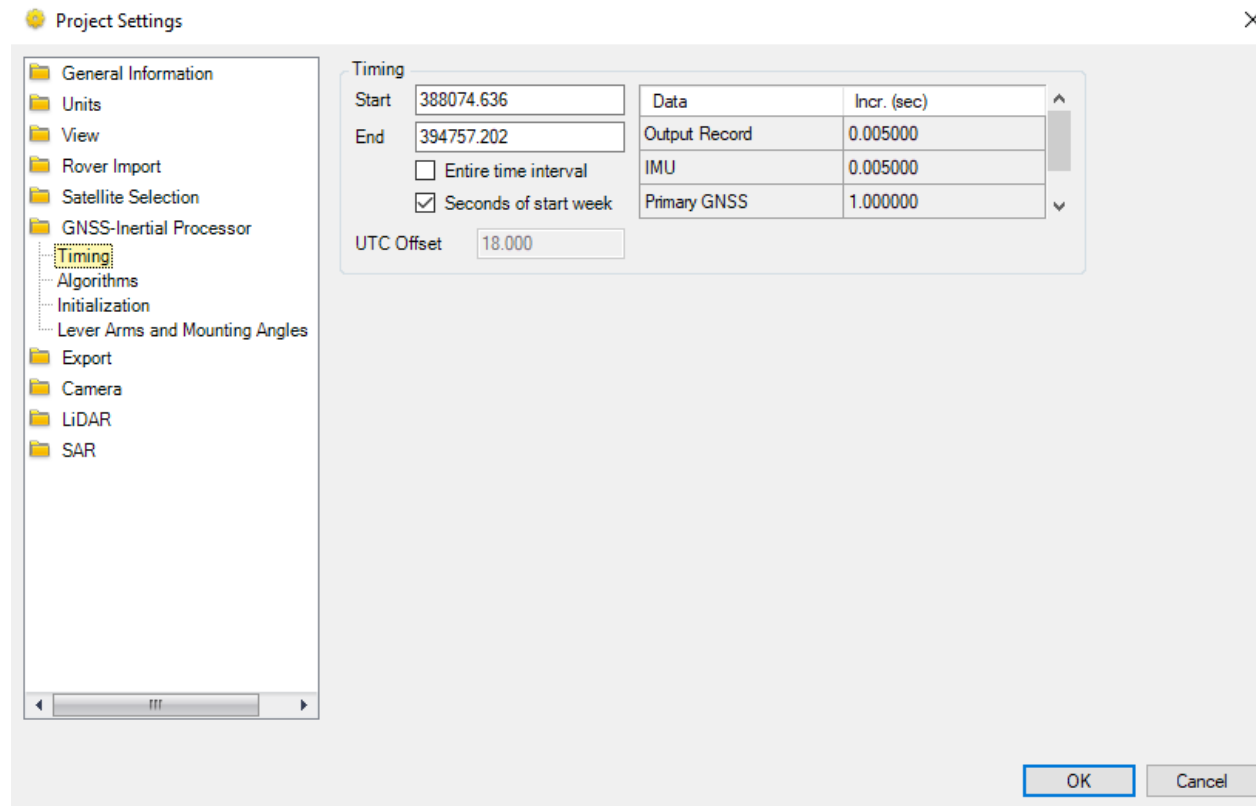
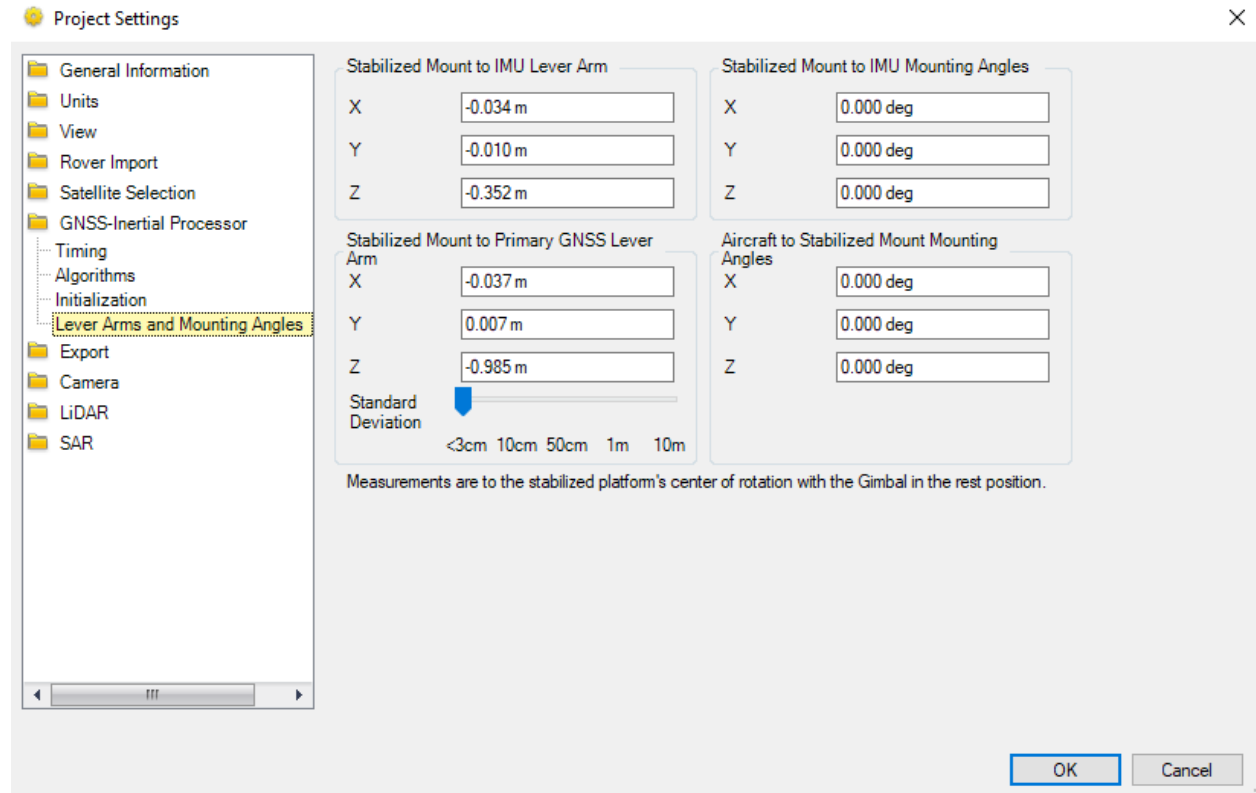


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

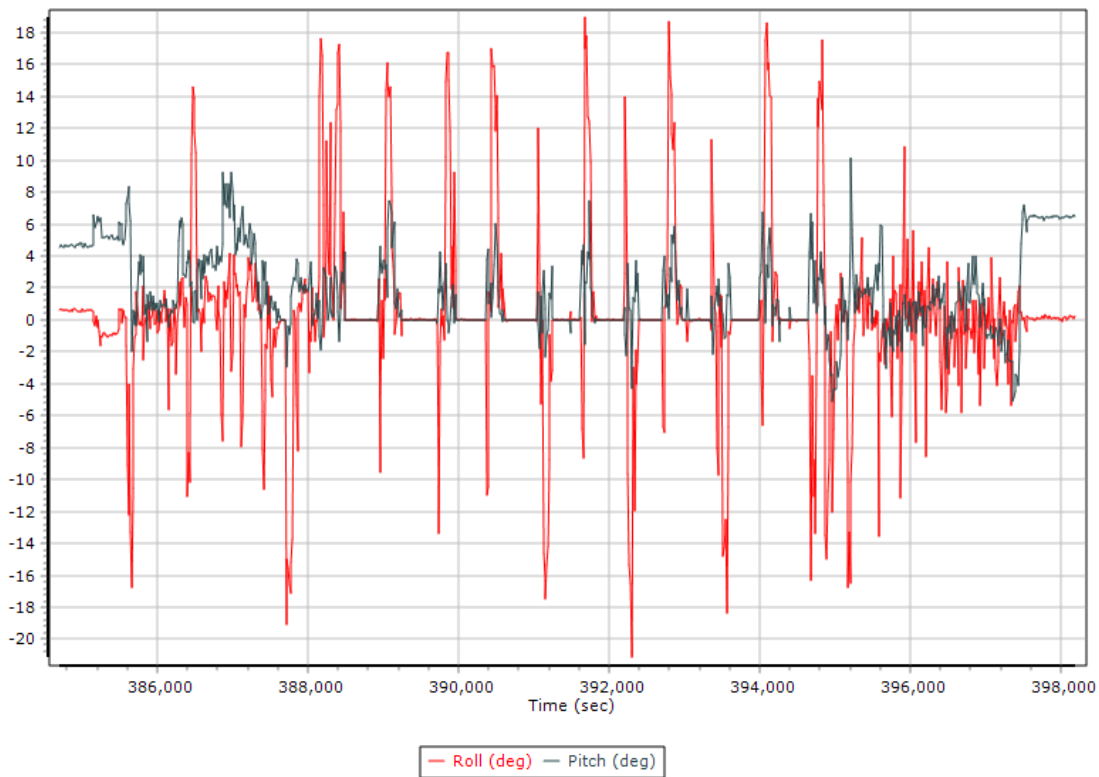
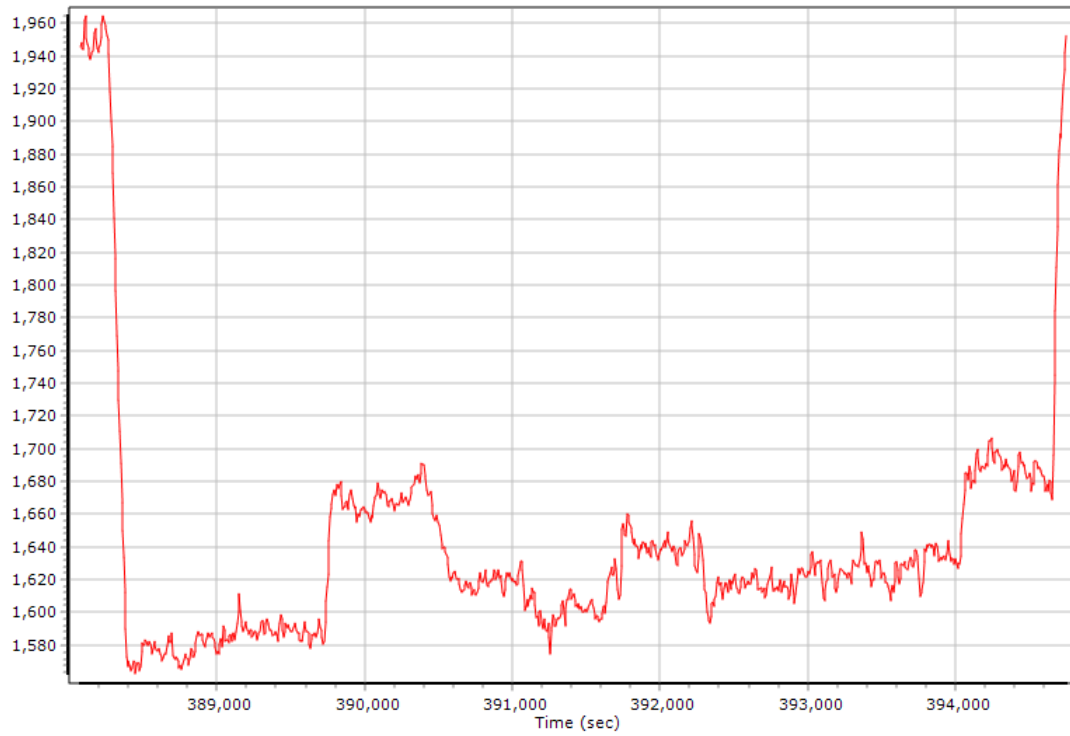


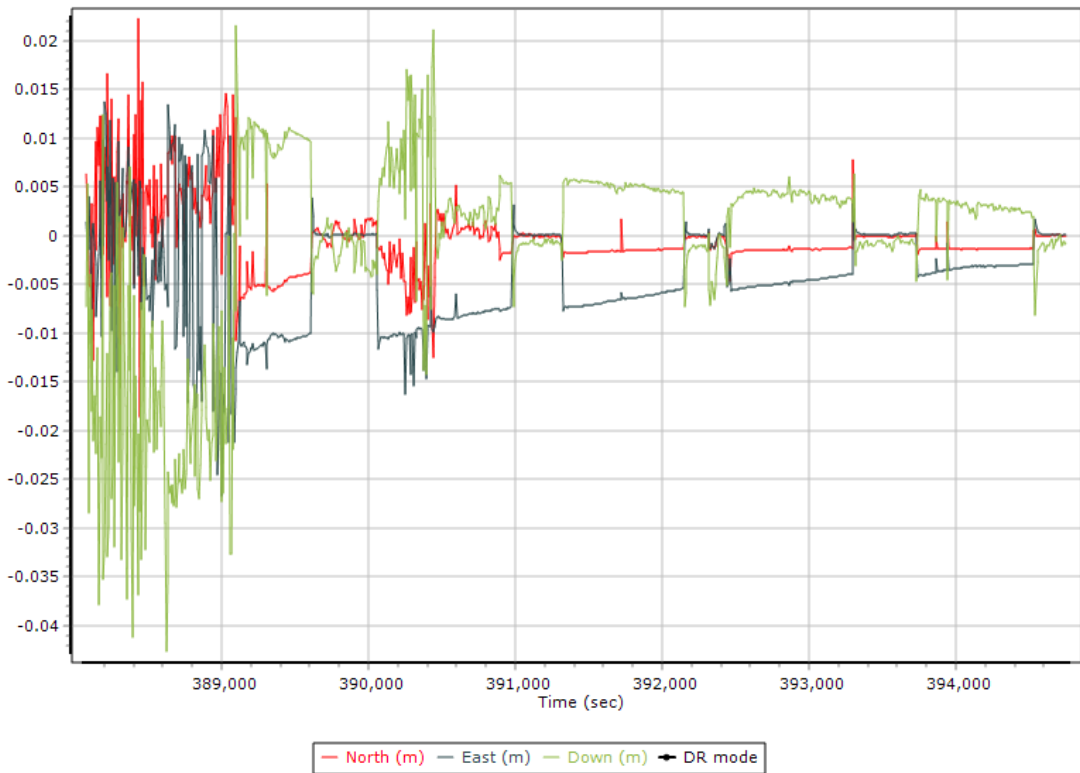
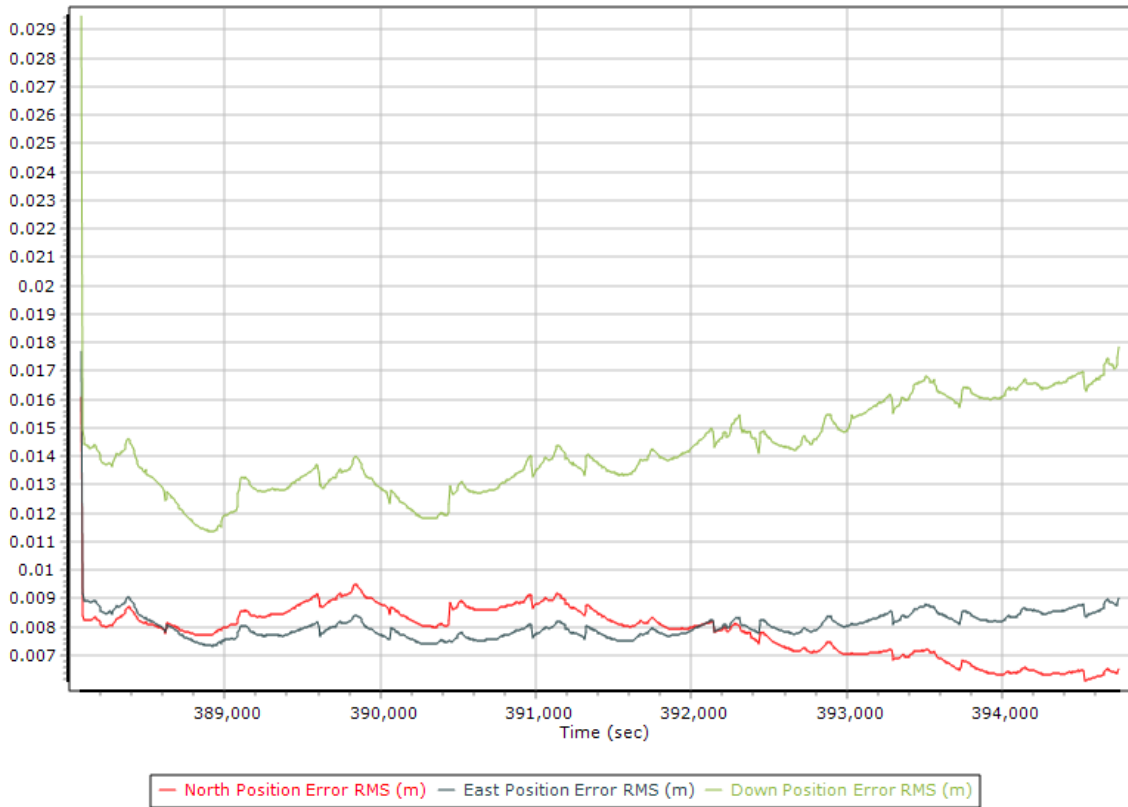
RBV18137A

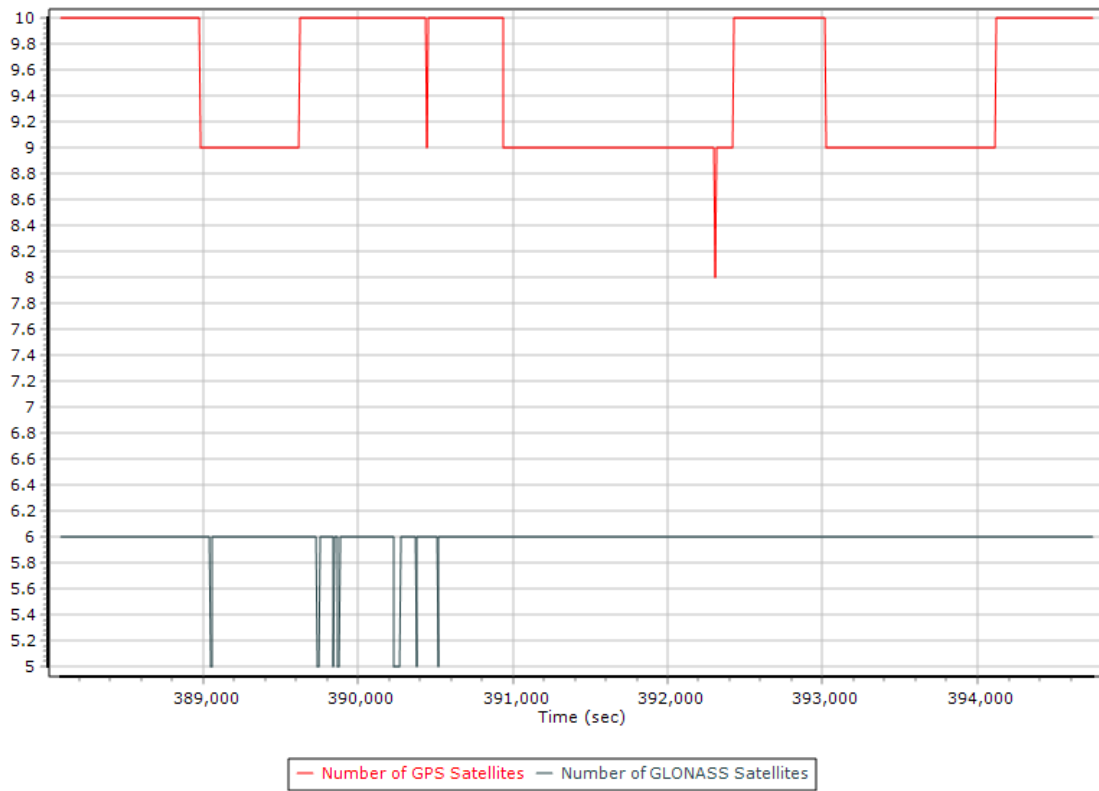




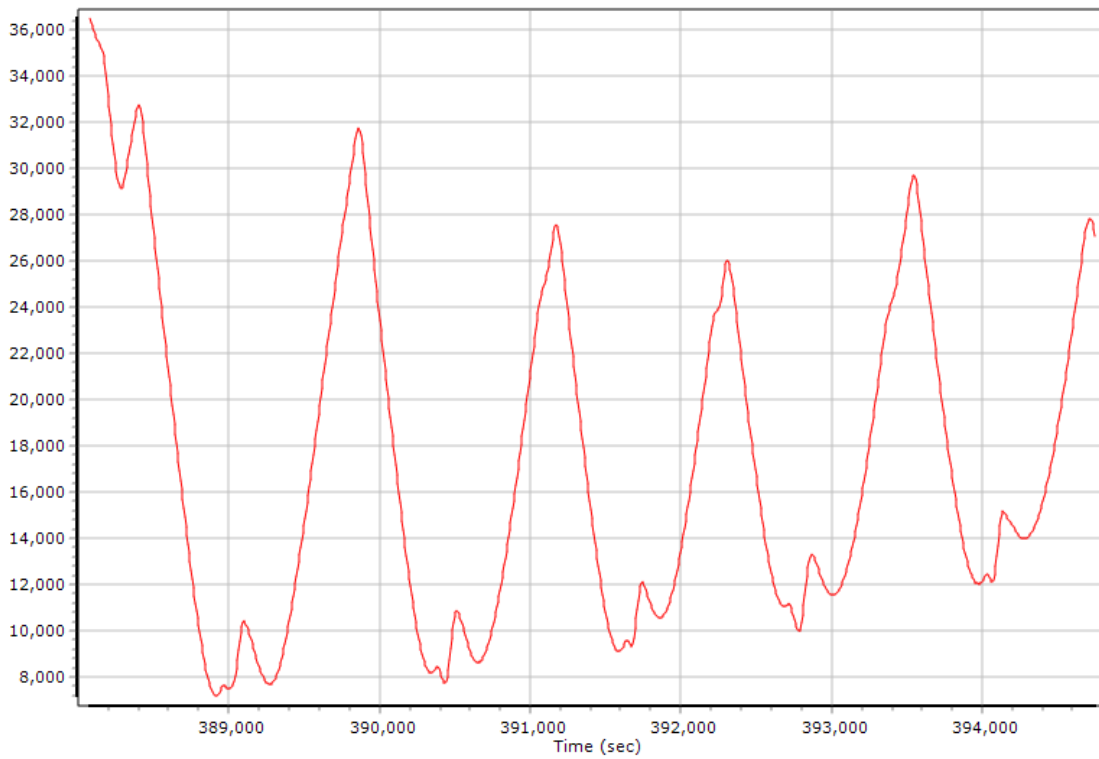
Altitude (m)

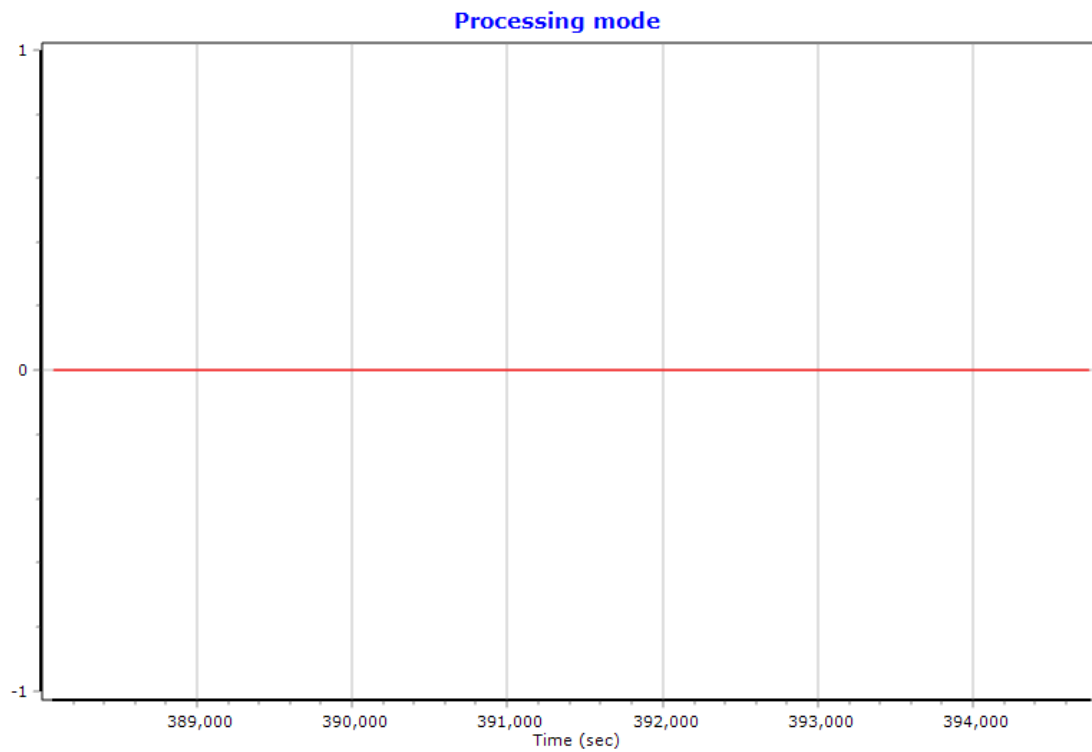
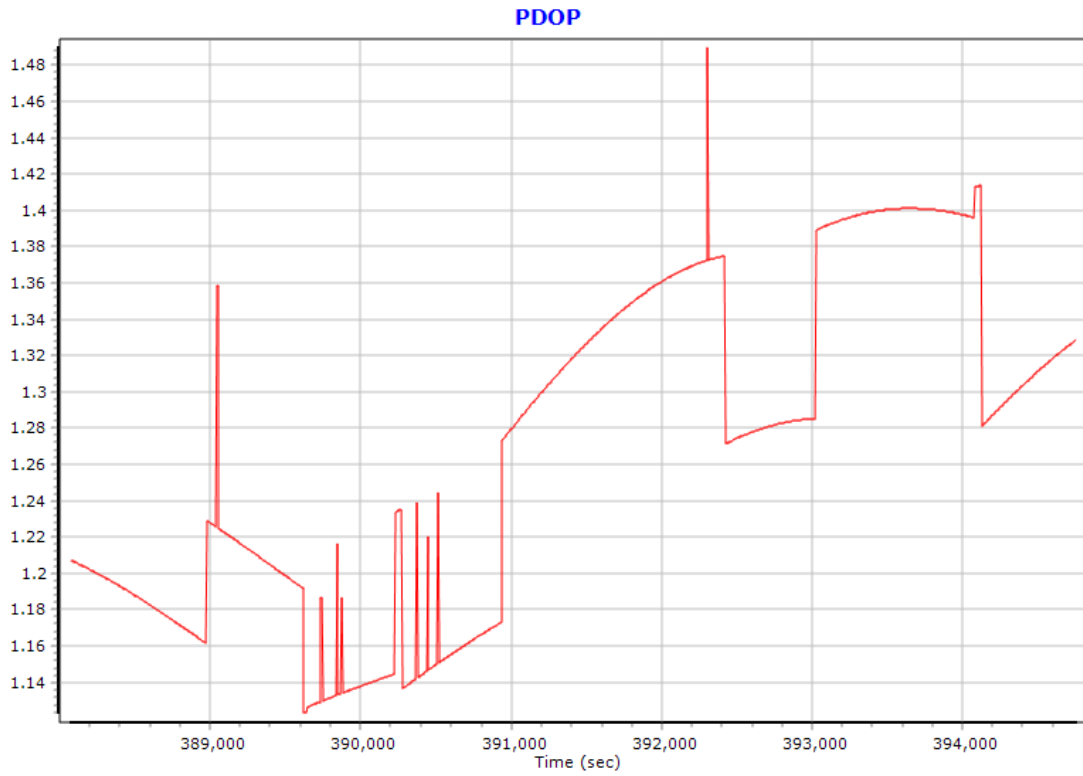






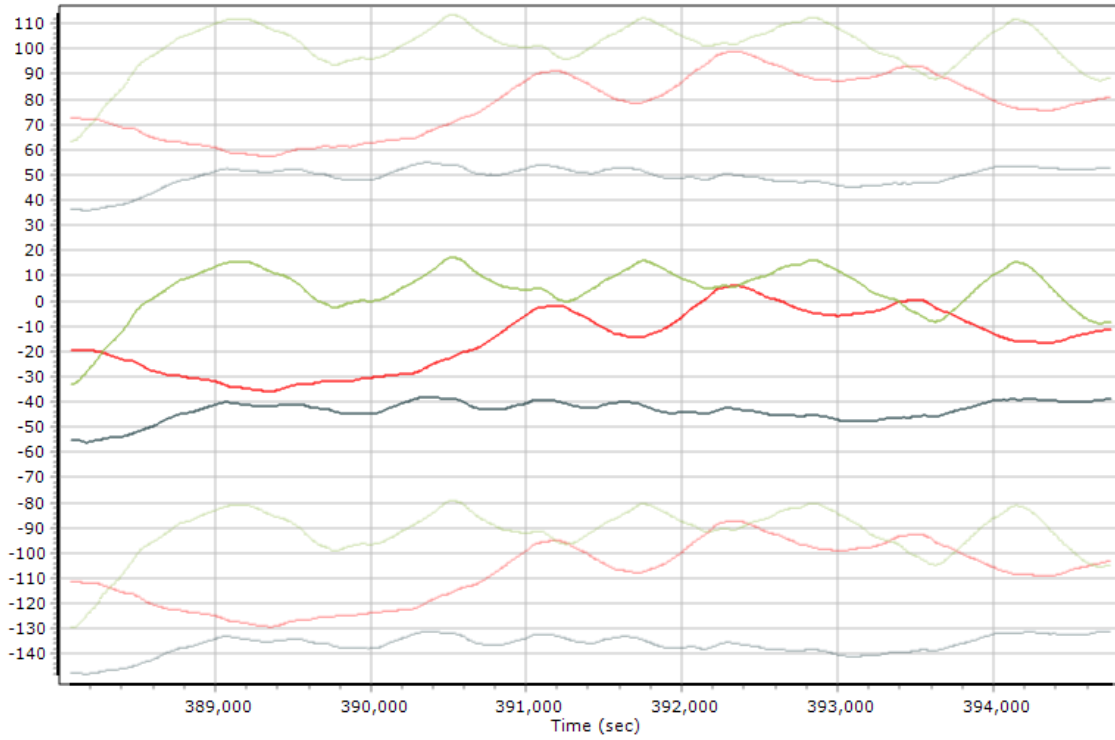
Baseline Length (m)



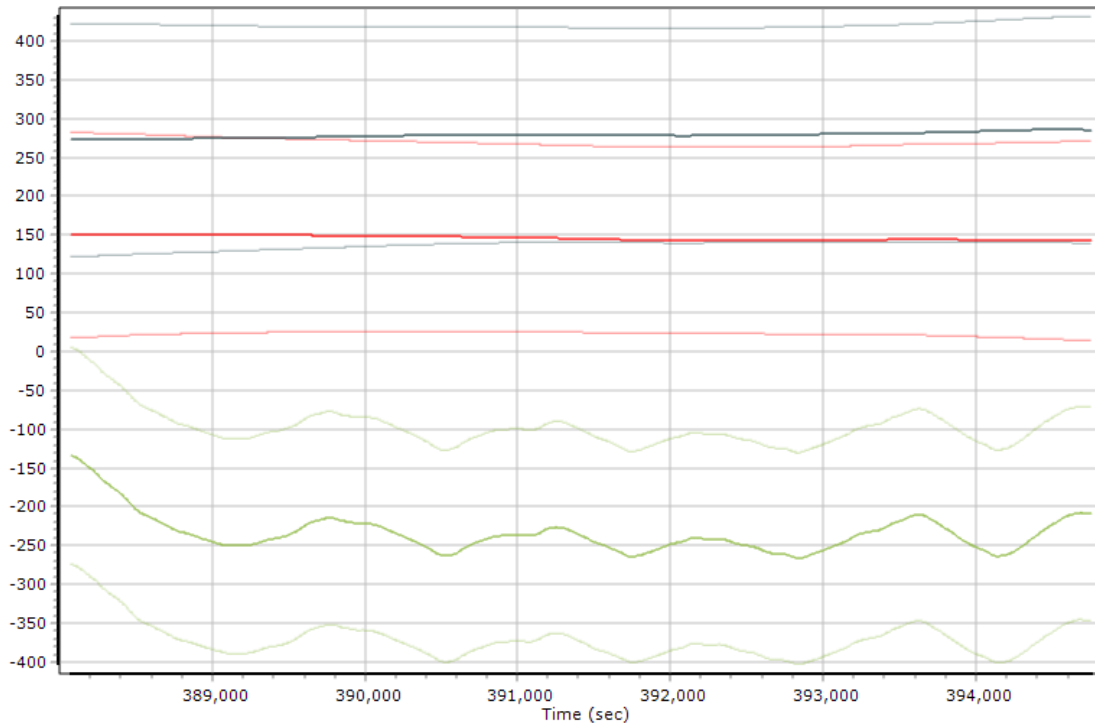


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

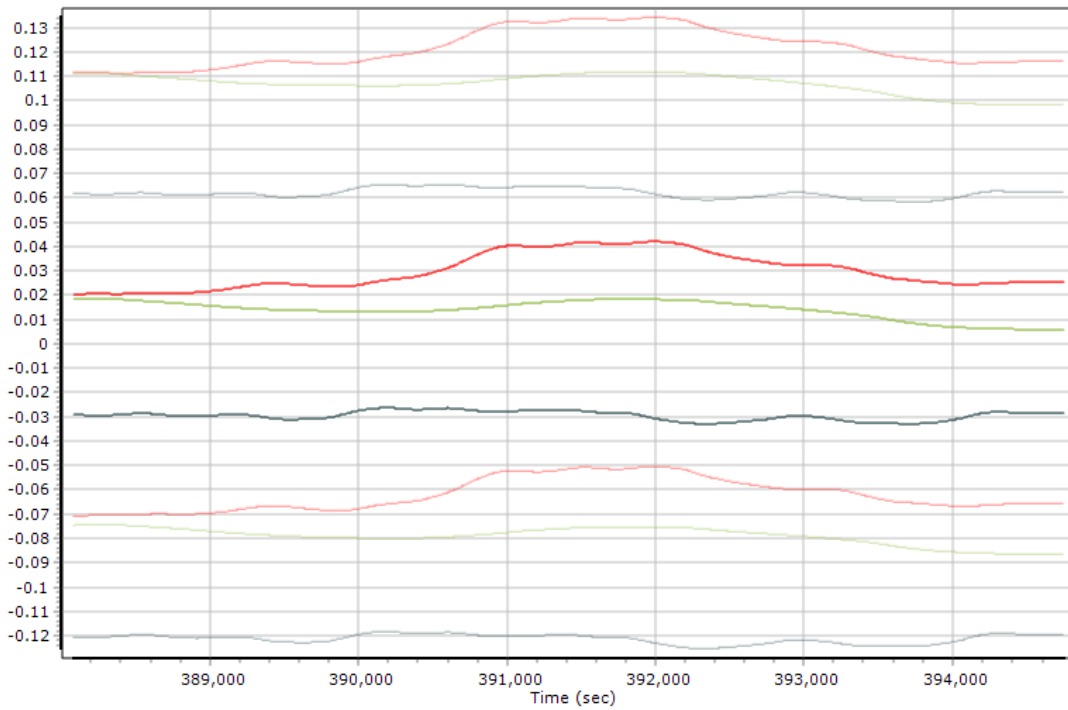
Sensor Errors



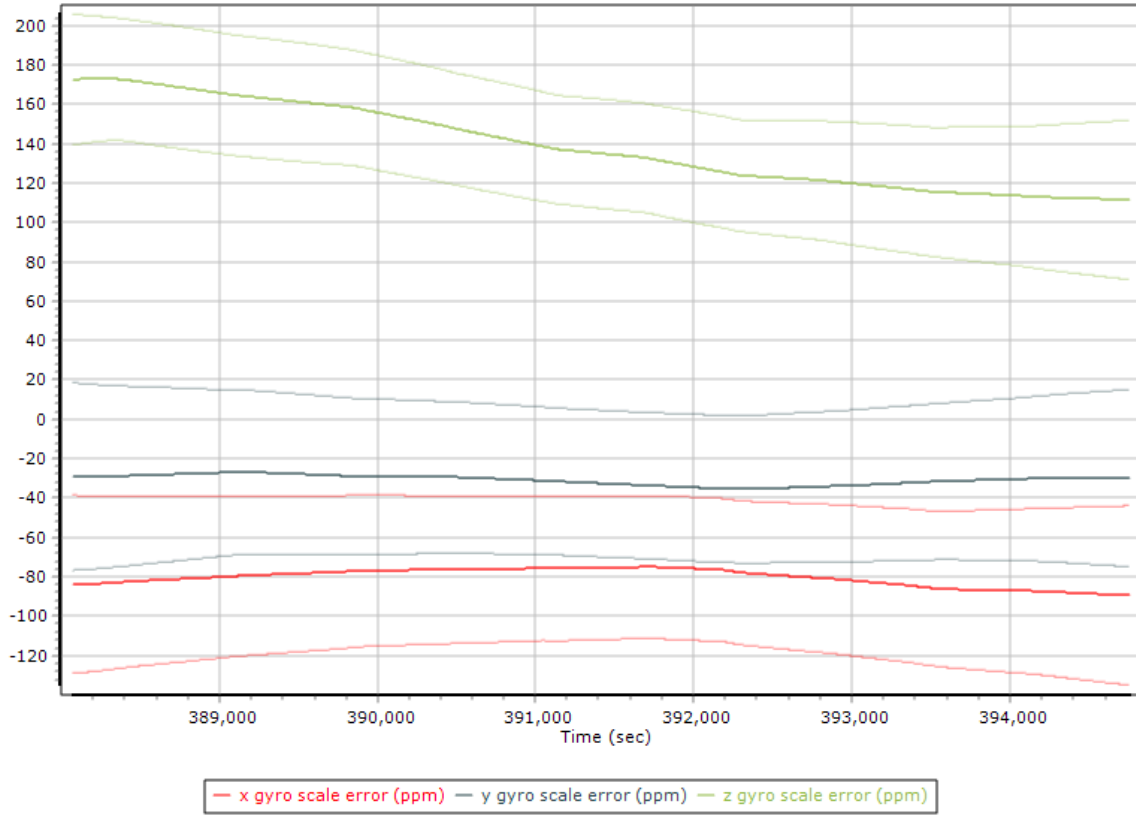
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)



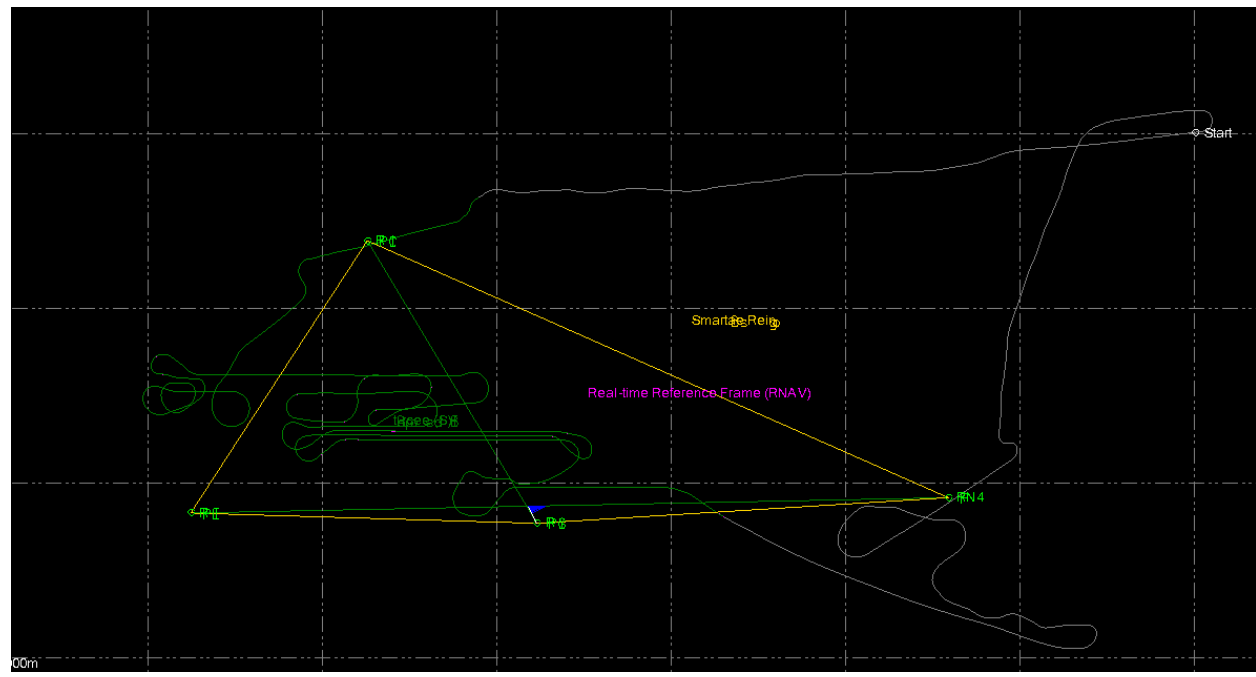
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



RBV18138A



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: -0.034 m
Y: -0.010 m
Z: -0.352 m

Stabilized Mount to IMU Mounting Angles
X: 0.000 deg
Y: 0.000 deg
Z: 0.000 deg

Stabilized Mount to Primary GNSS Lever Arm
X: -0.037 m
Y: 0.007 m
Z: -0.985 m

Aircraft to Stabilized Mount Mounting Angles
X: 0.000 deg
Y: 0.000 deg
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

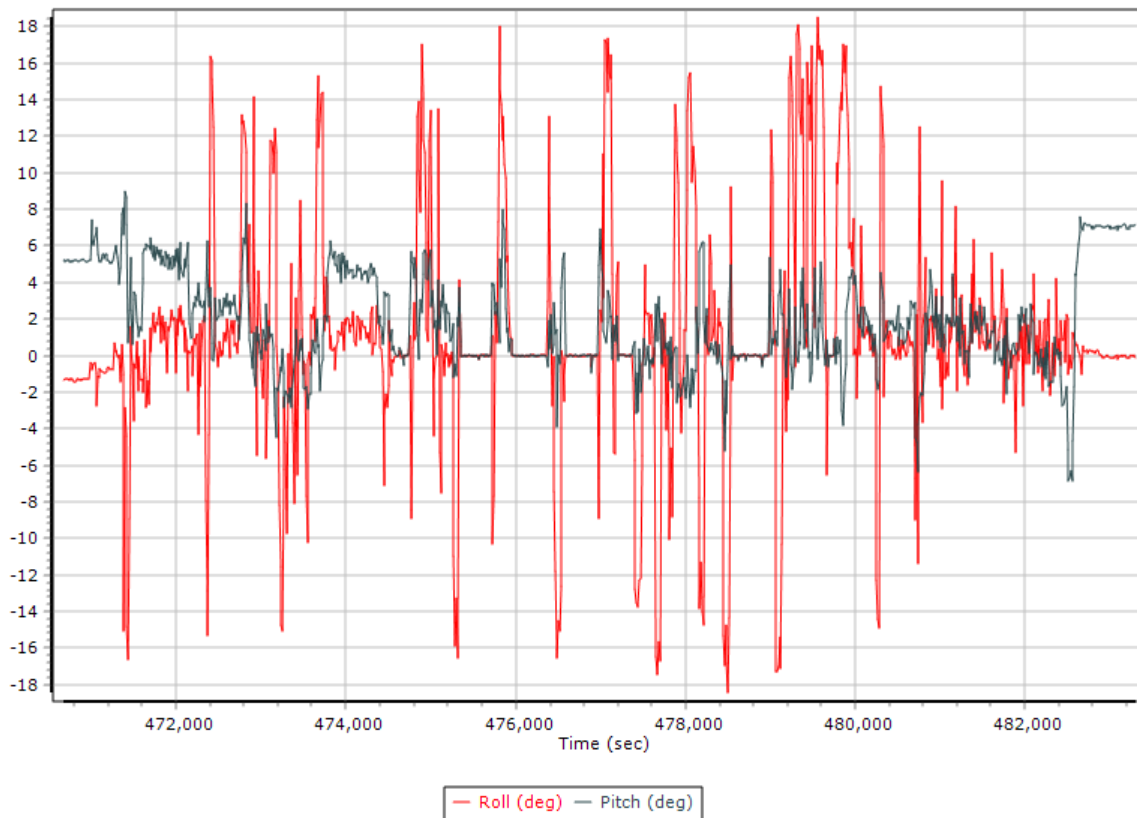
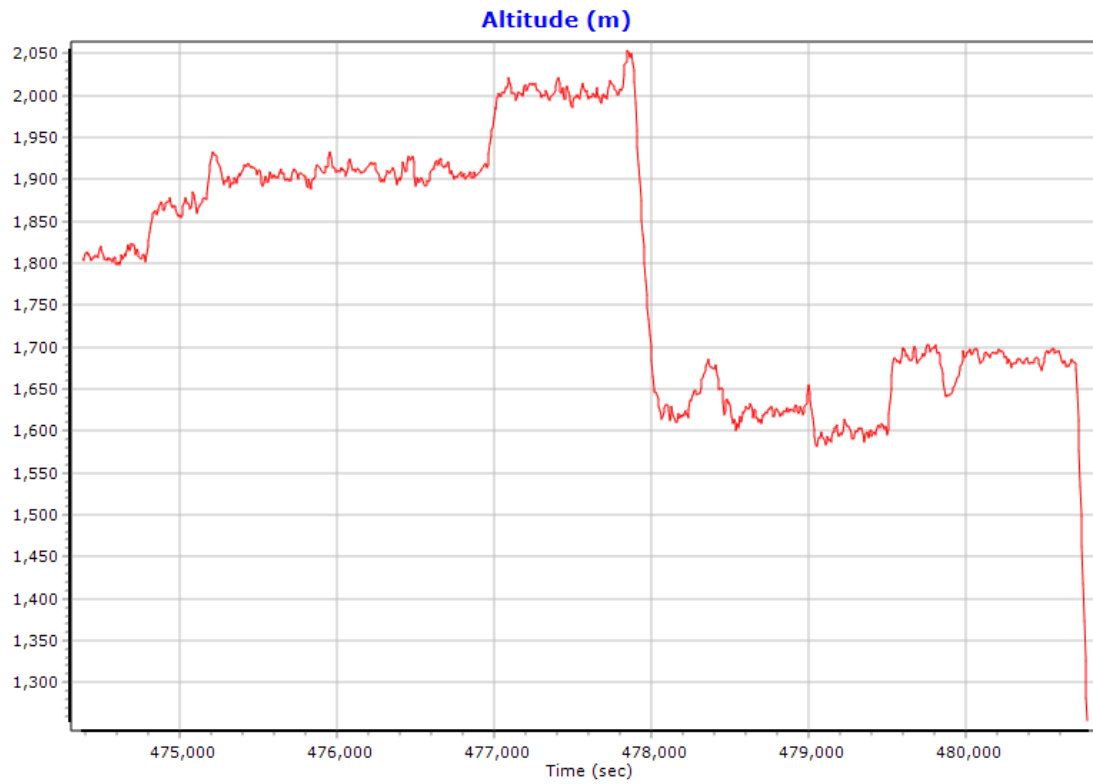
Project Settings

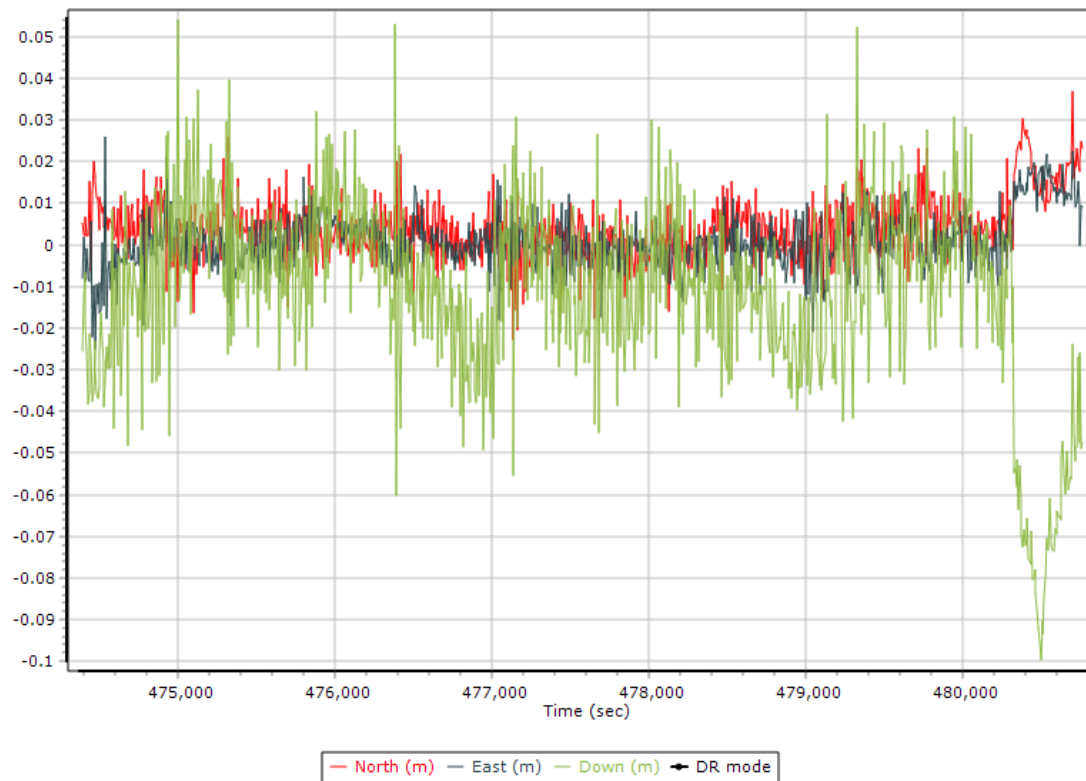
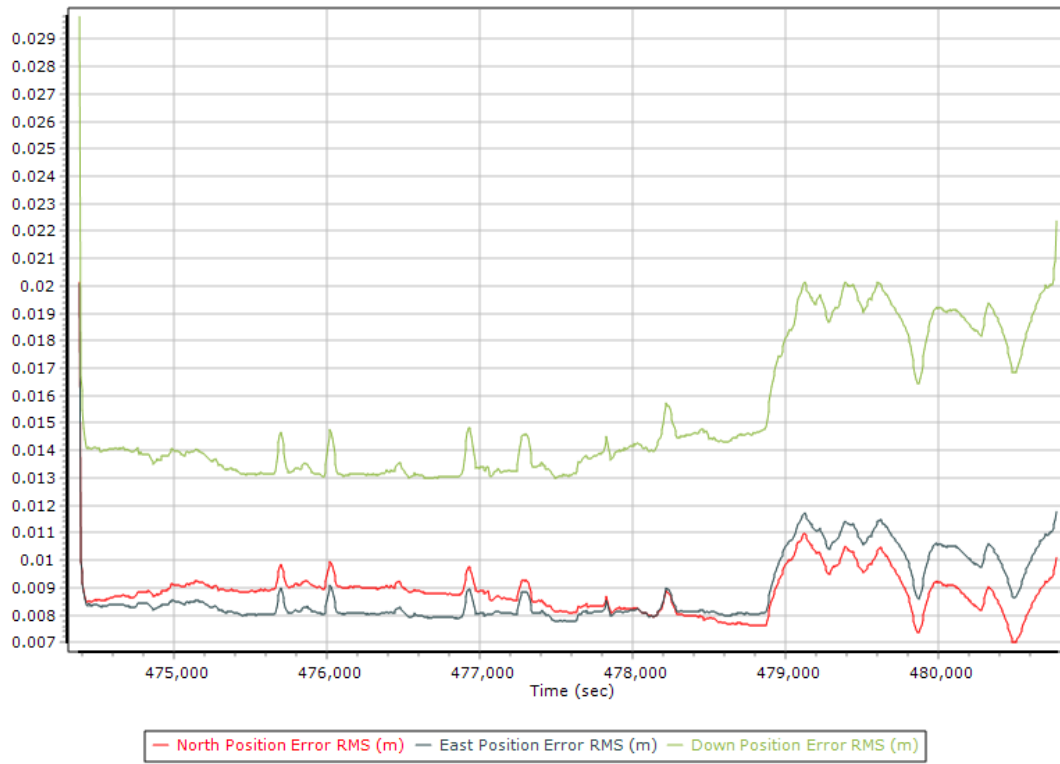
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
 Timing
 Algorithms
 Initialization
 Lever Arms and Mounting Angles
Export
Camera
LiDAR
SAR

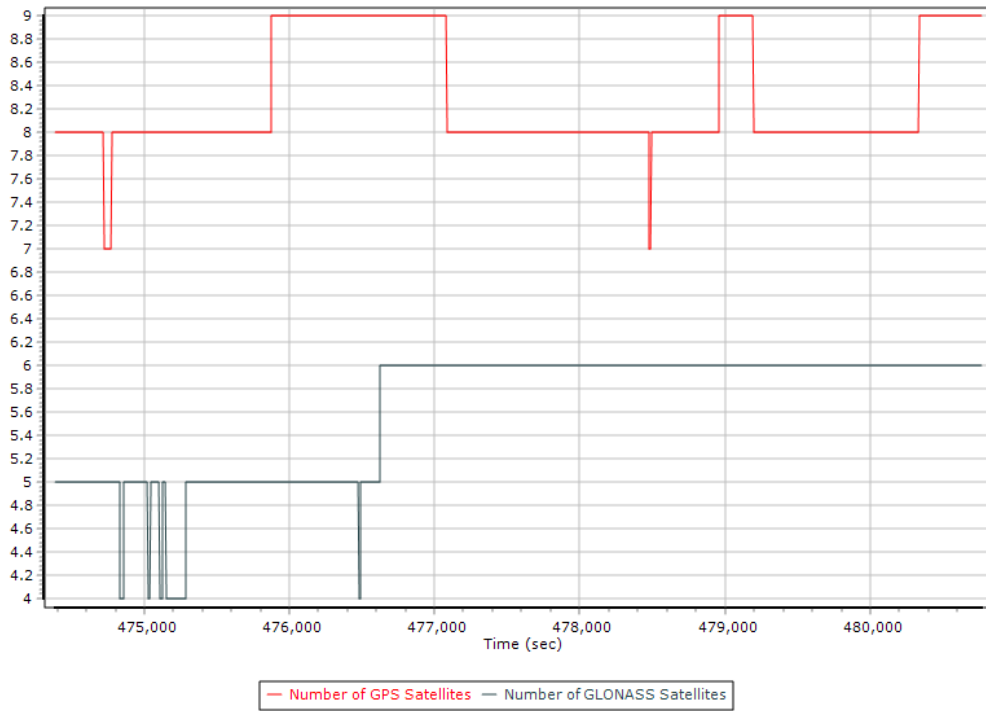
Timing
Start: 474382.754
End: 480777.253
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

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

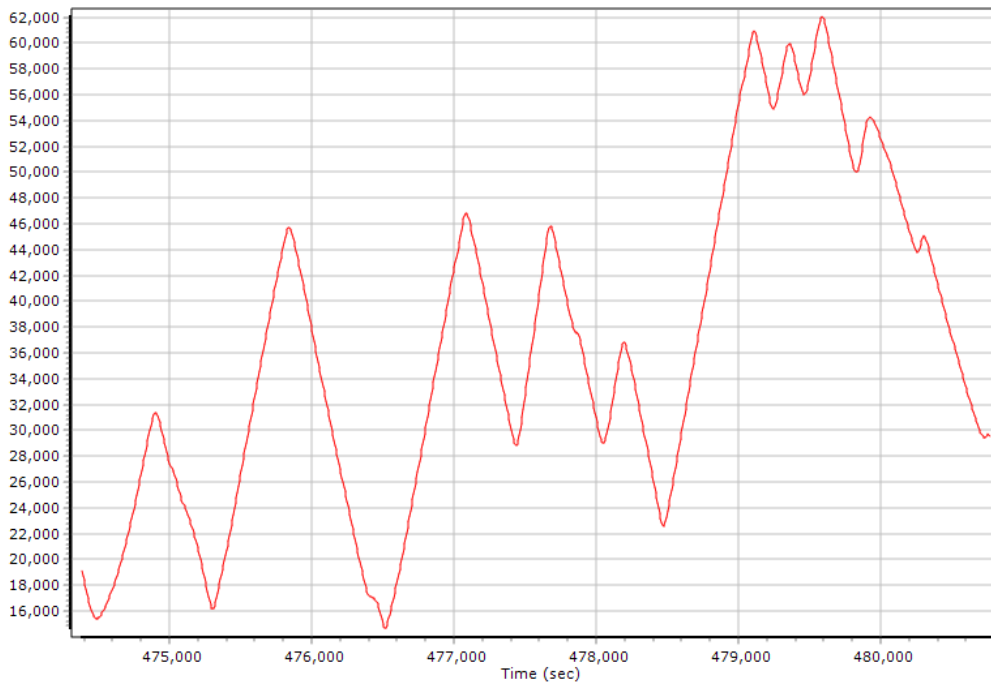
OK Cancel



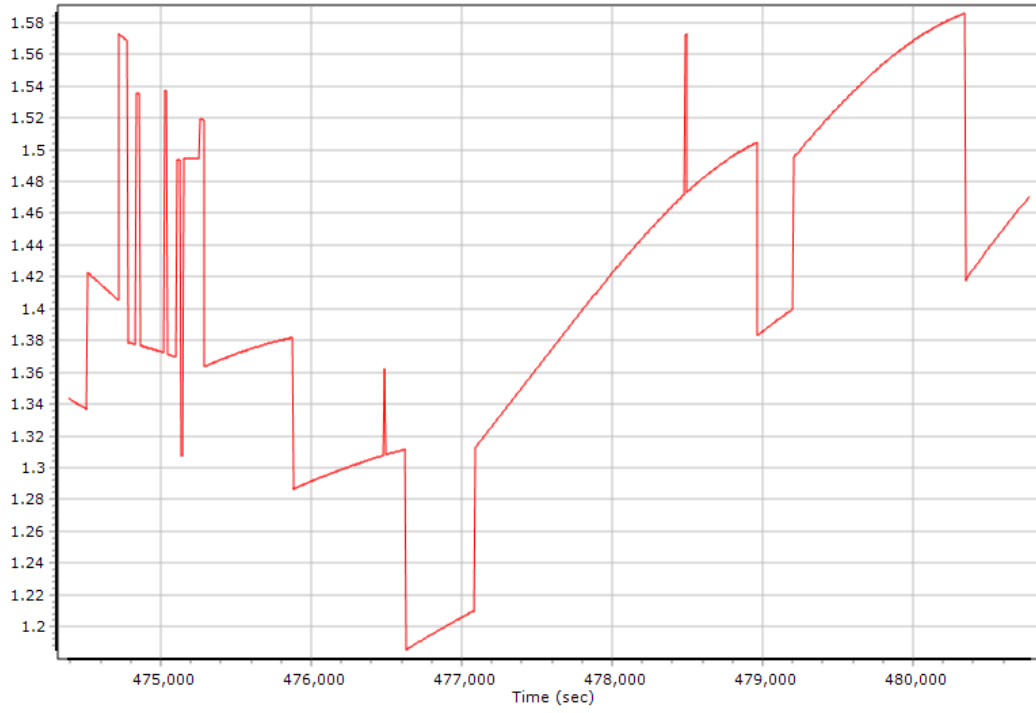




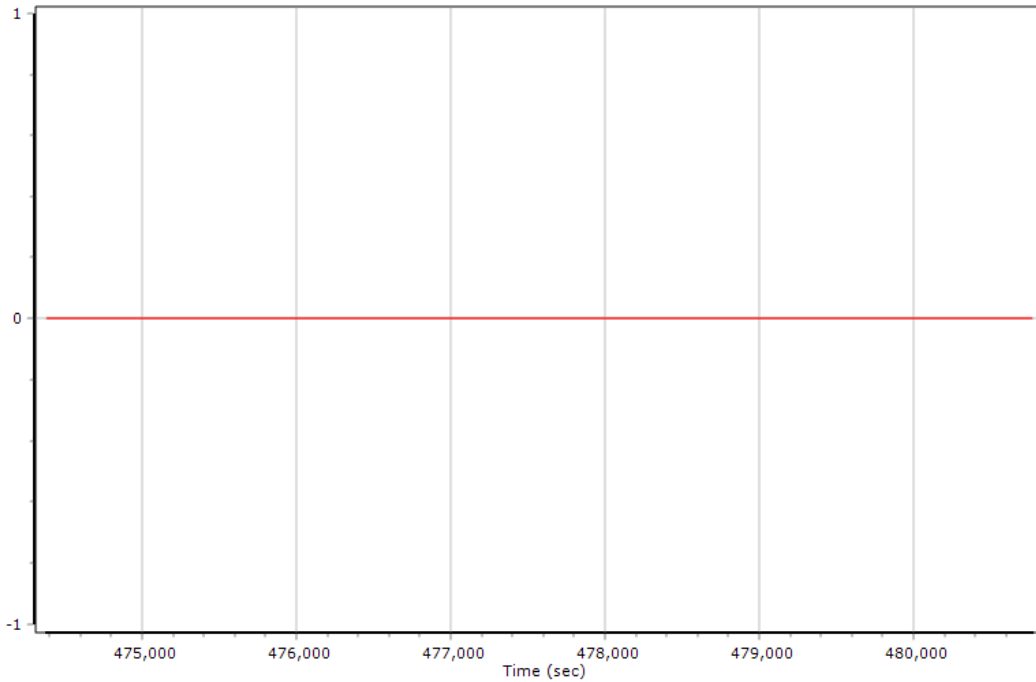
Baseline Length (m)



PDOP

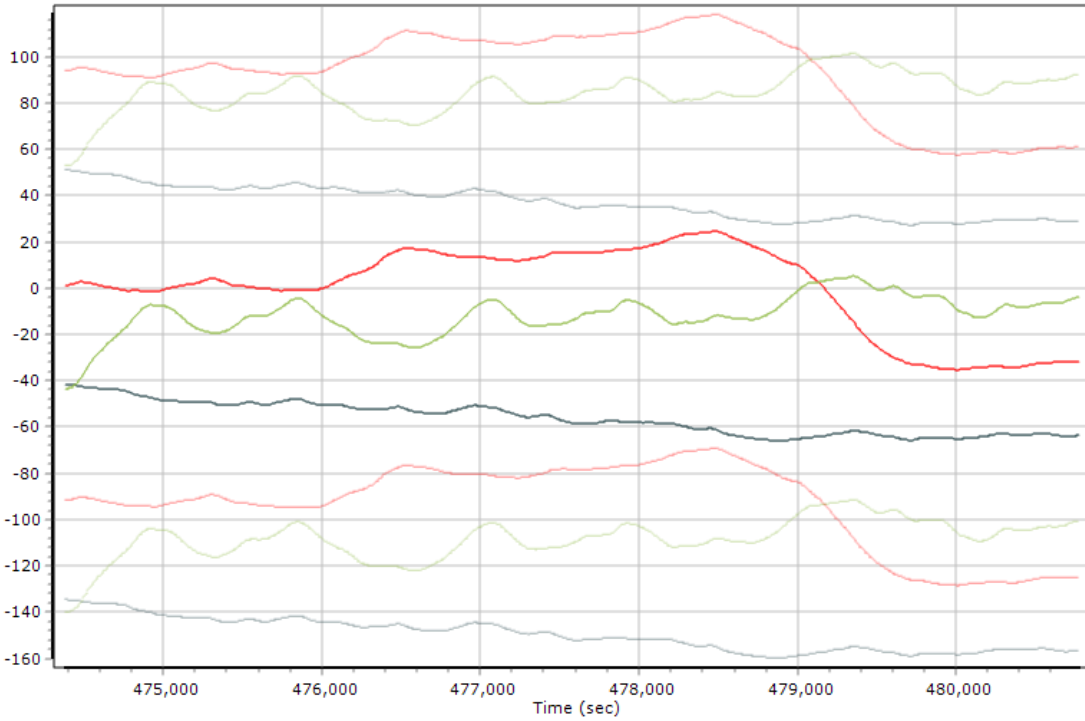


Processing mode

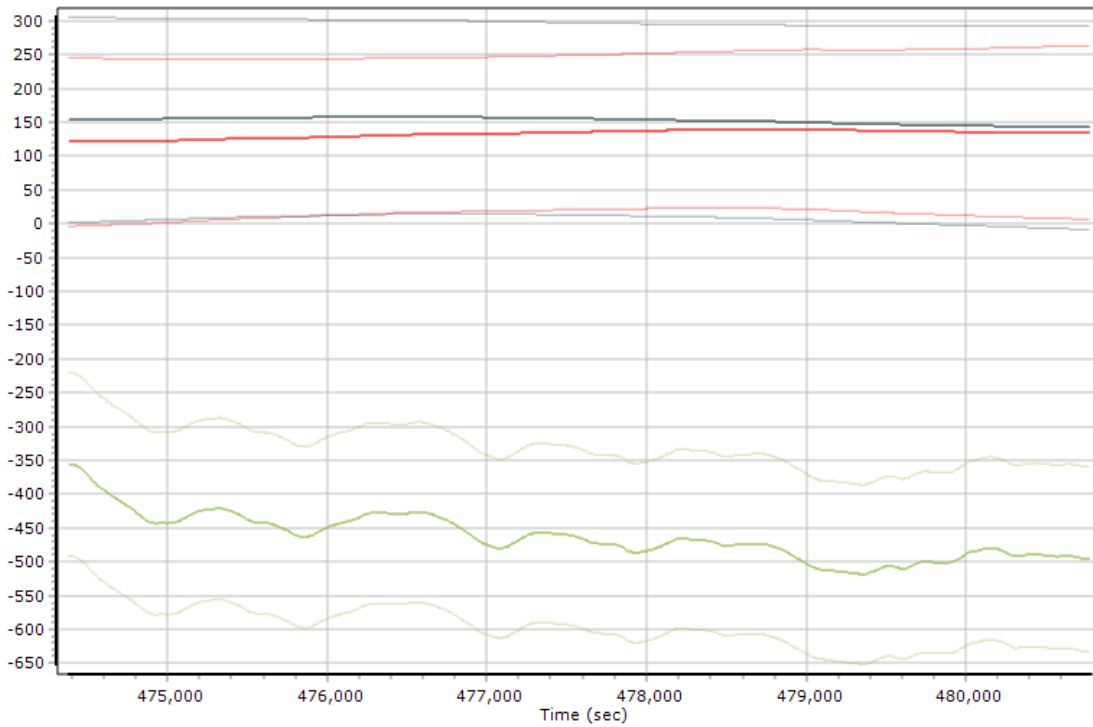


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

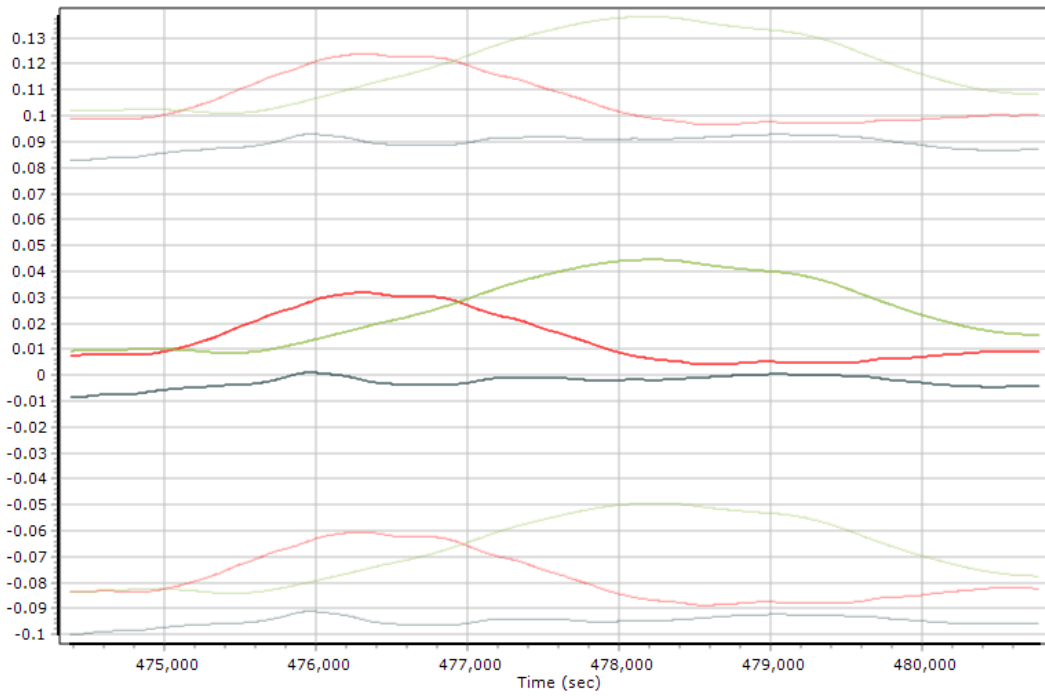
Snesor Errors



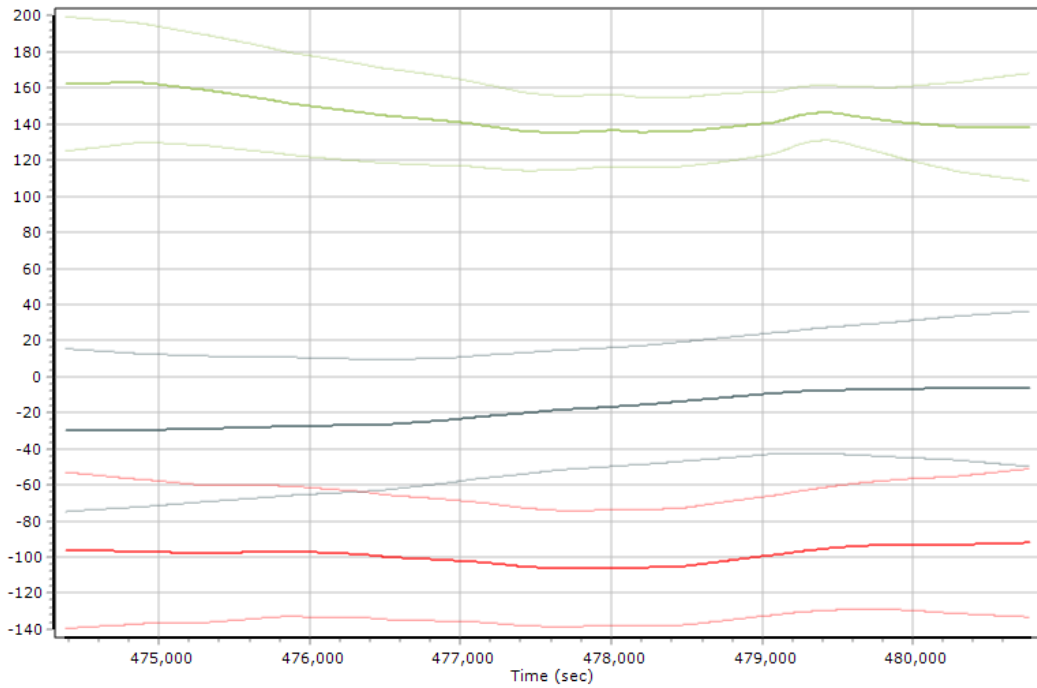
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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

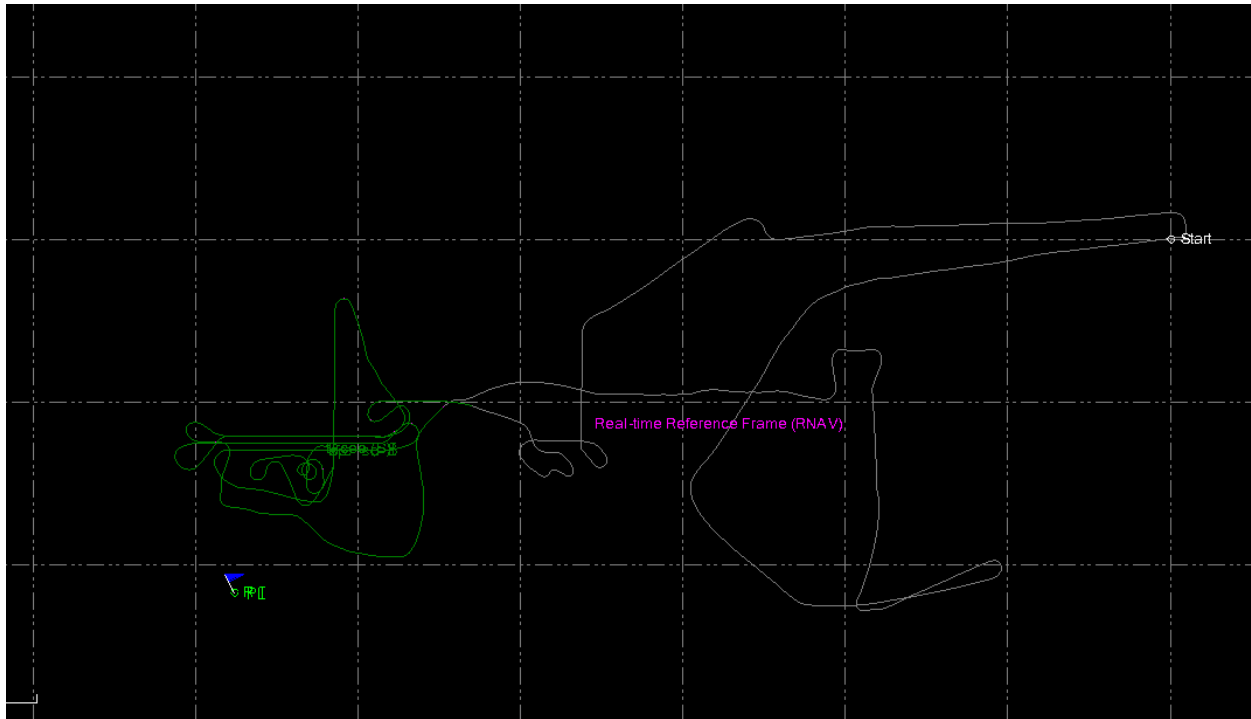


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



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

RBV18139A



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

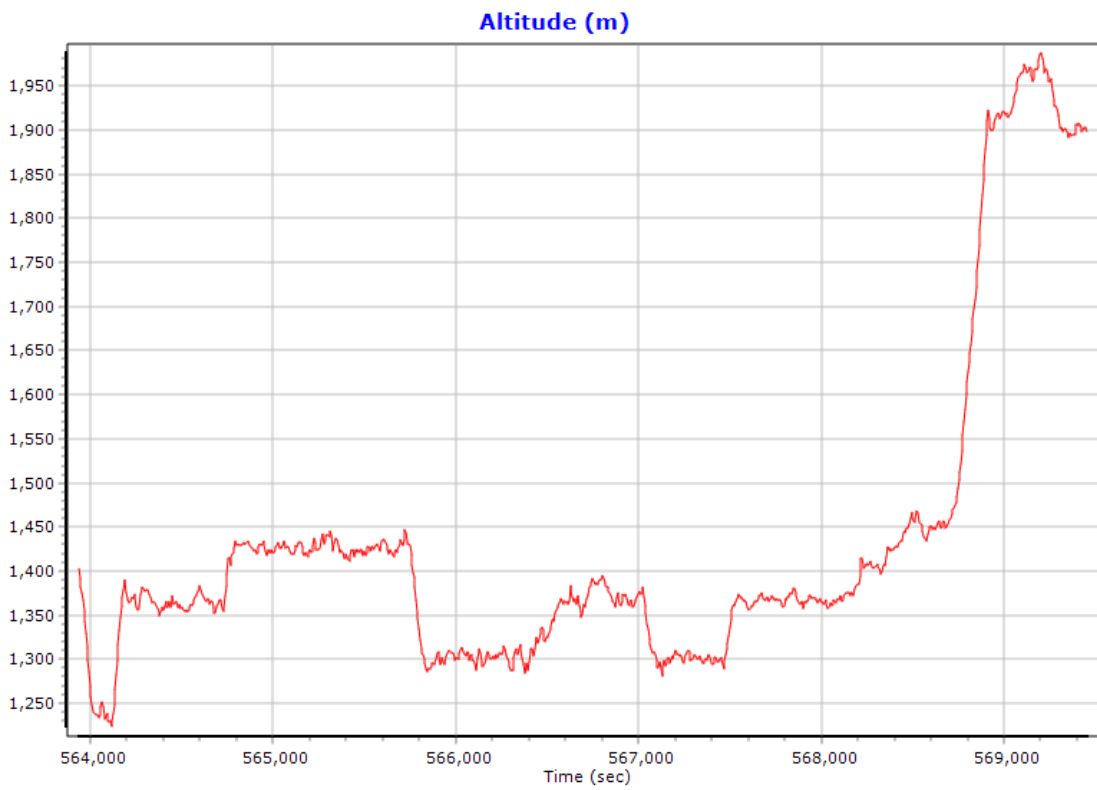
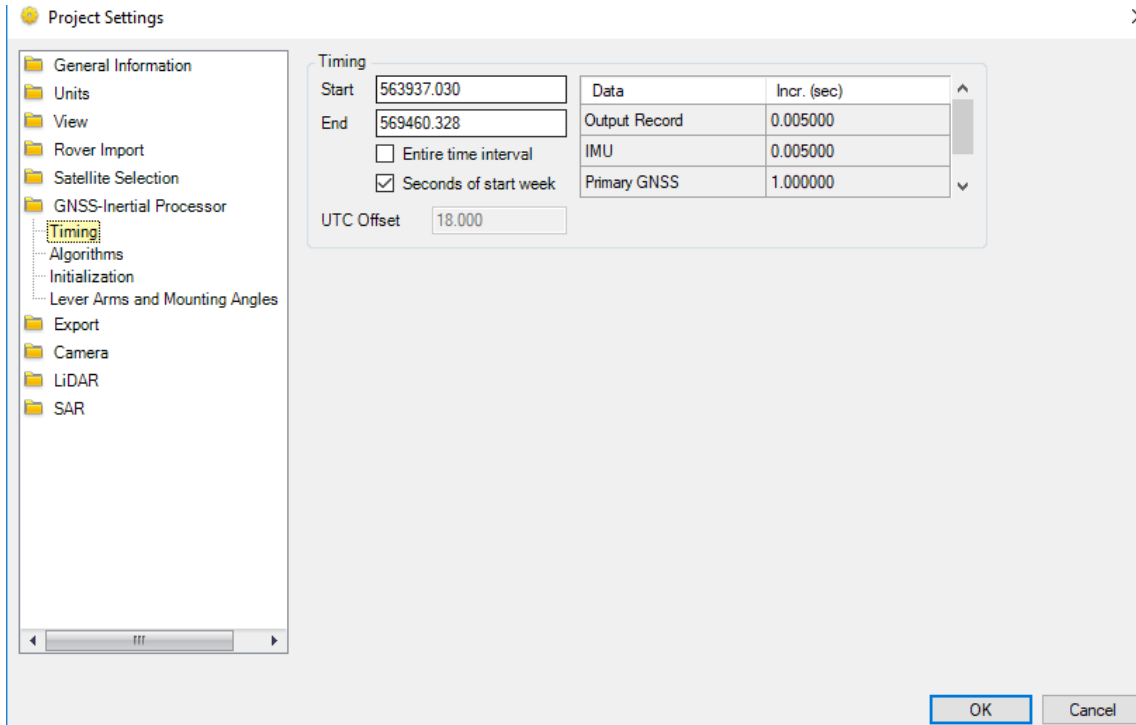
Stabilized Mount to IMU Lever Arm	Stabilized Mount to IMU Mounting Angles
X: -0.034 m	X: 0.000 deg
Y: -0.010 m	Y: 0.000 deg
Z: -0.352 m	Z: 0.000 deg

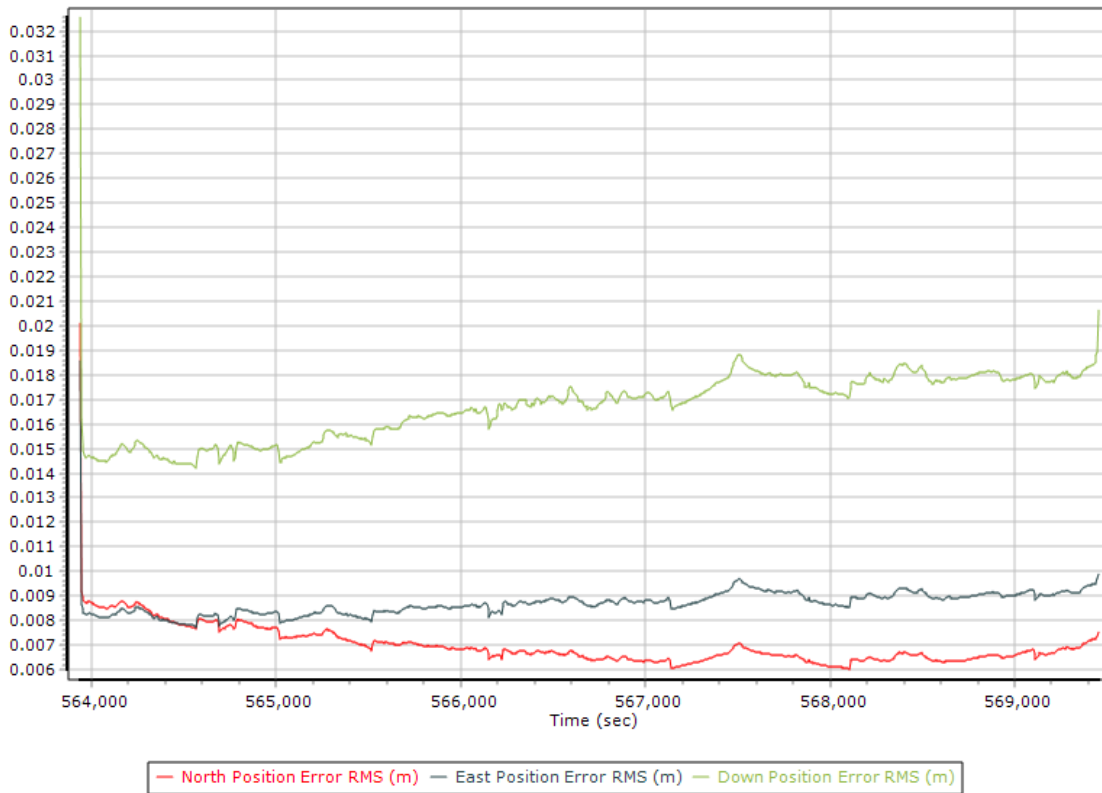
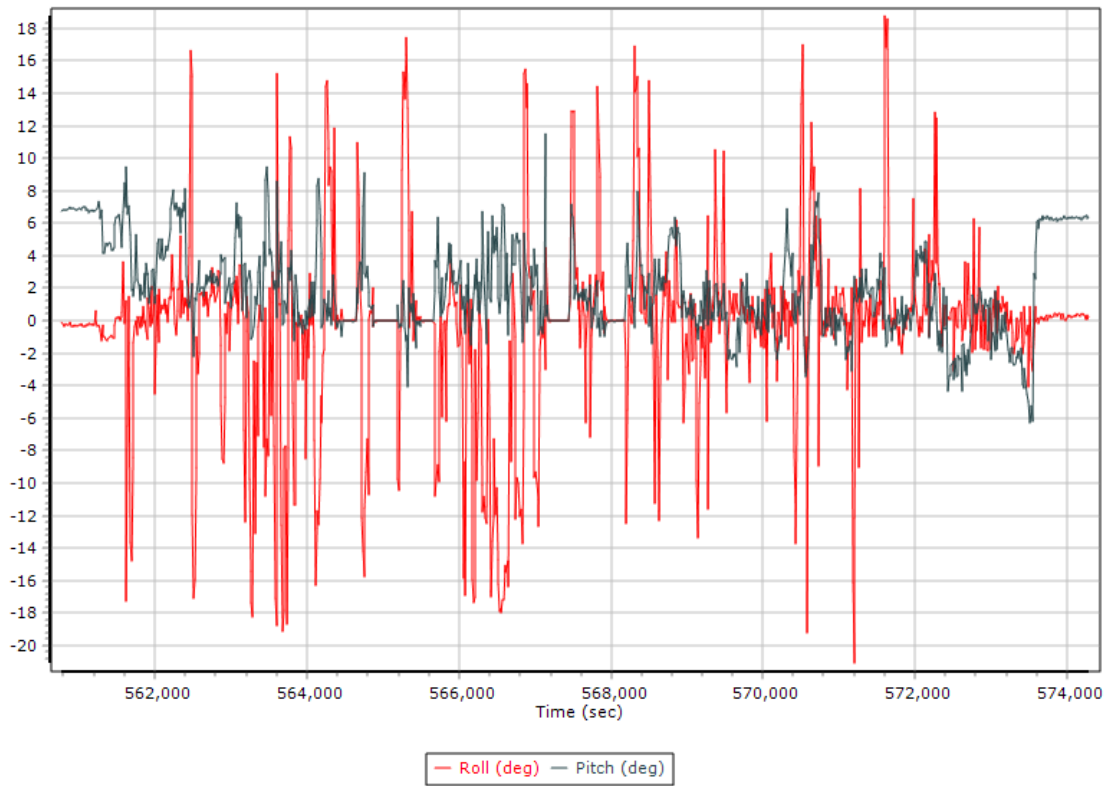
Stabilized Mount to Primary GNSS Lever Arm	Aircraft to Stabilized Mount Mounting Angles
X: -0.037 m	X: 0.000 deg
Y: 0.007 m	Y: 0.000 deg
Z: -0.985 m	Z: 0.000 deg

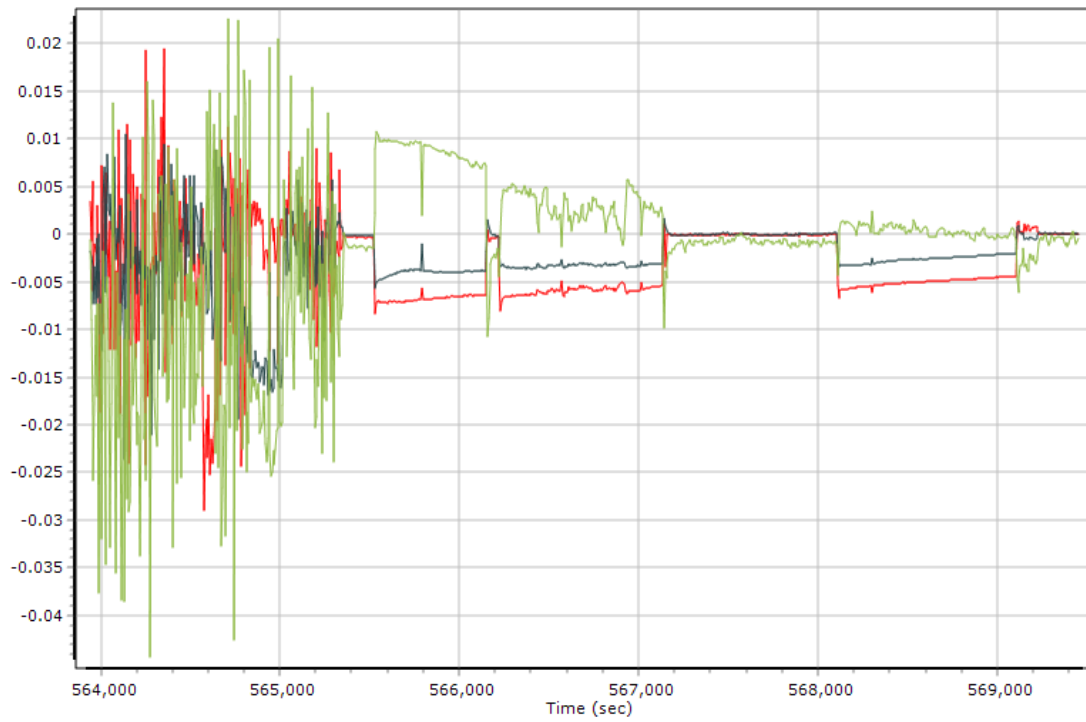
Standard Deviation: <3cm 10cm 50cm 1m 10m

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

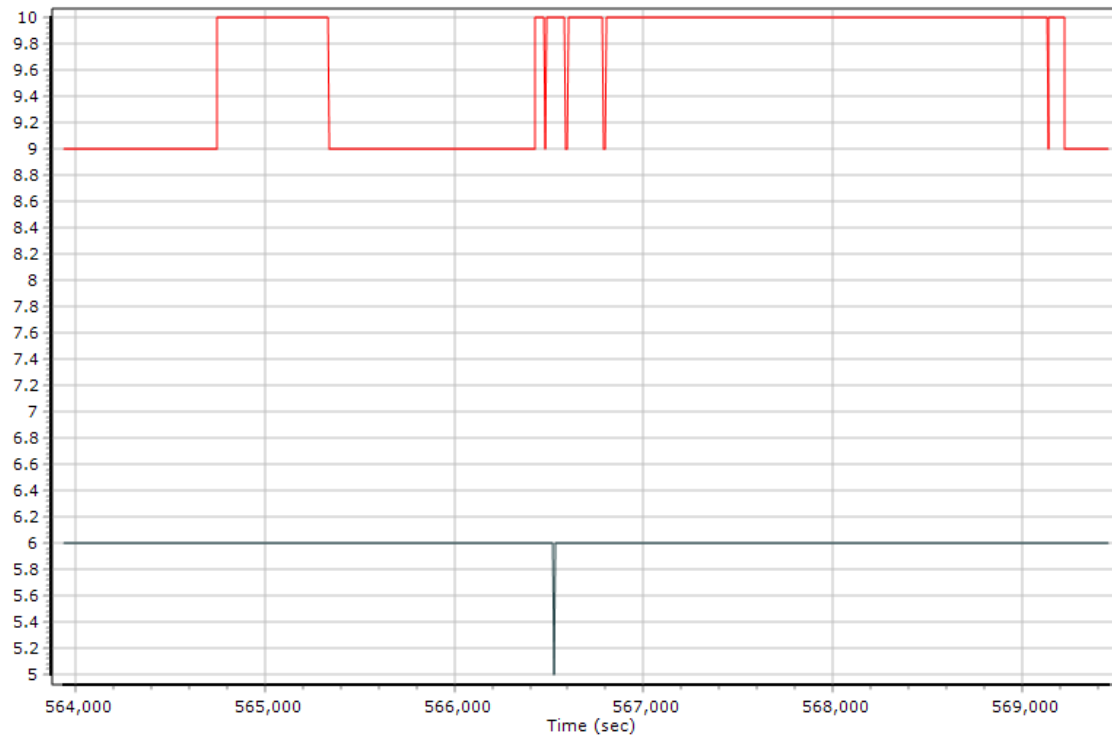
OK Cancel





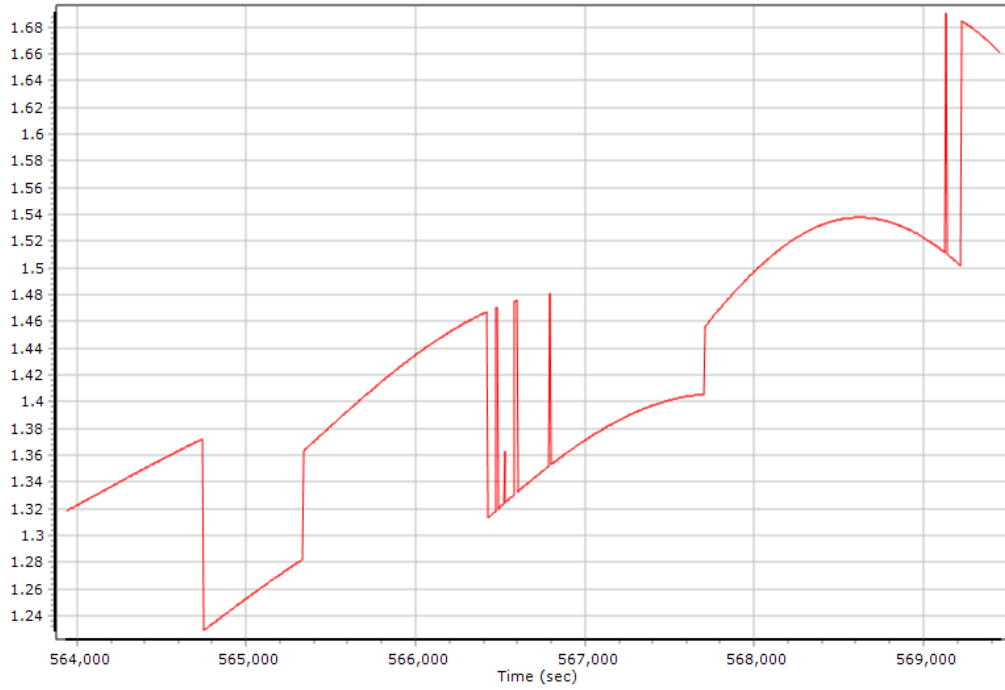


— North (m) — East (m) — Down (m) — DR mode

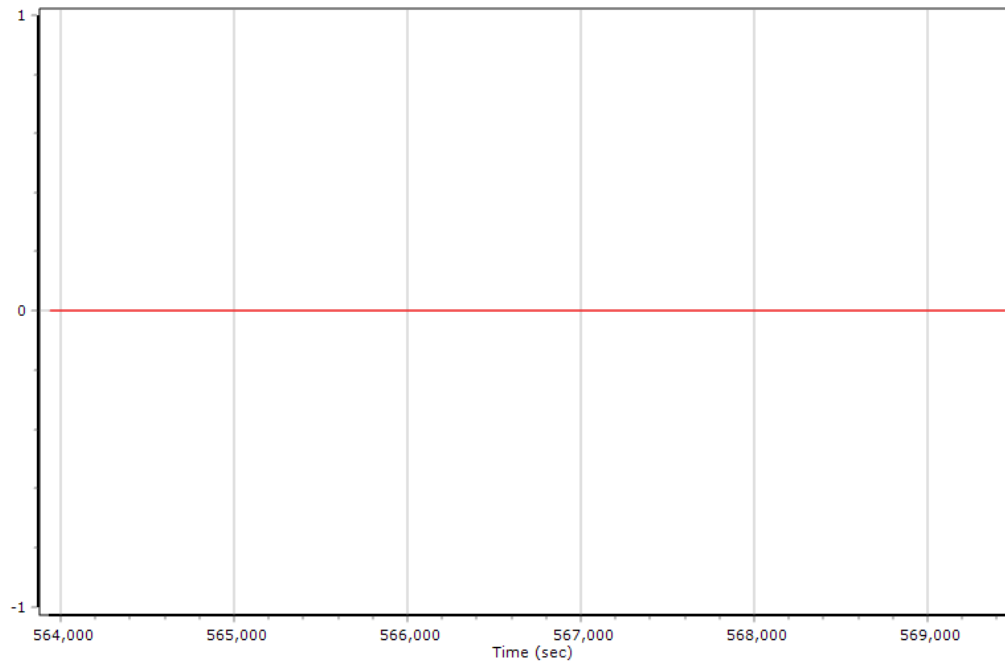


— Number of GPS Satellites — Number of GLONASS Satellites

PDOP

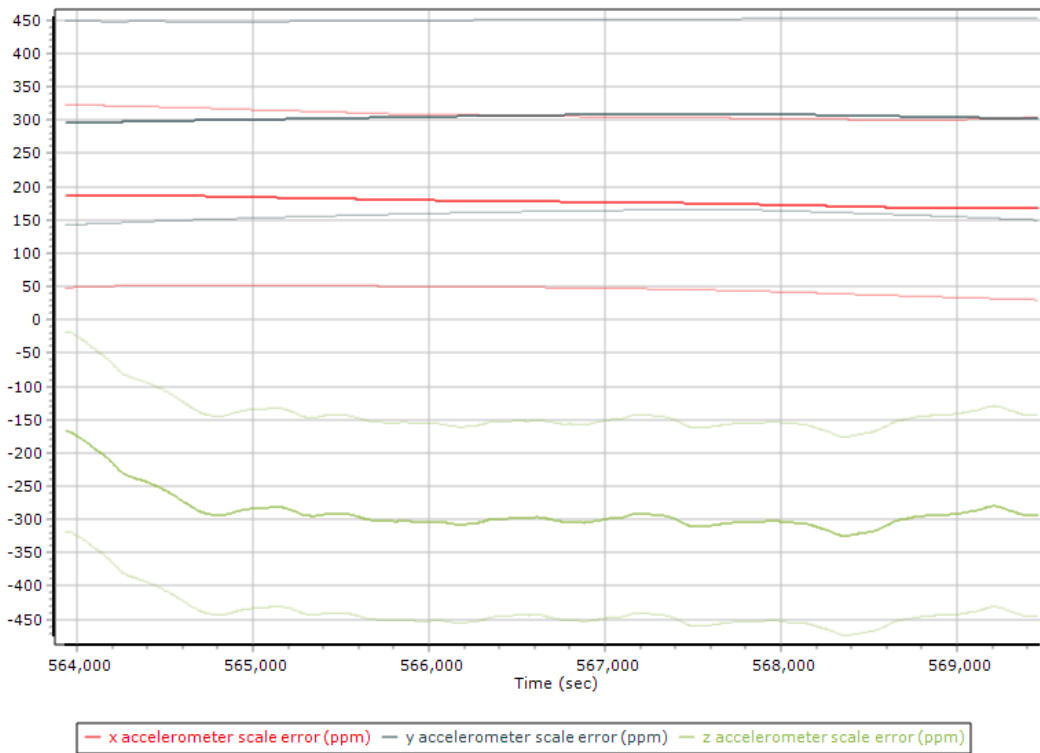
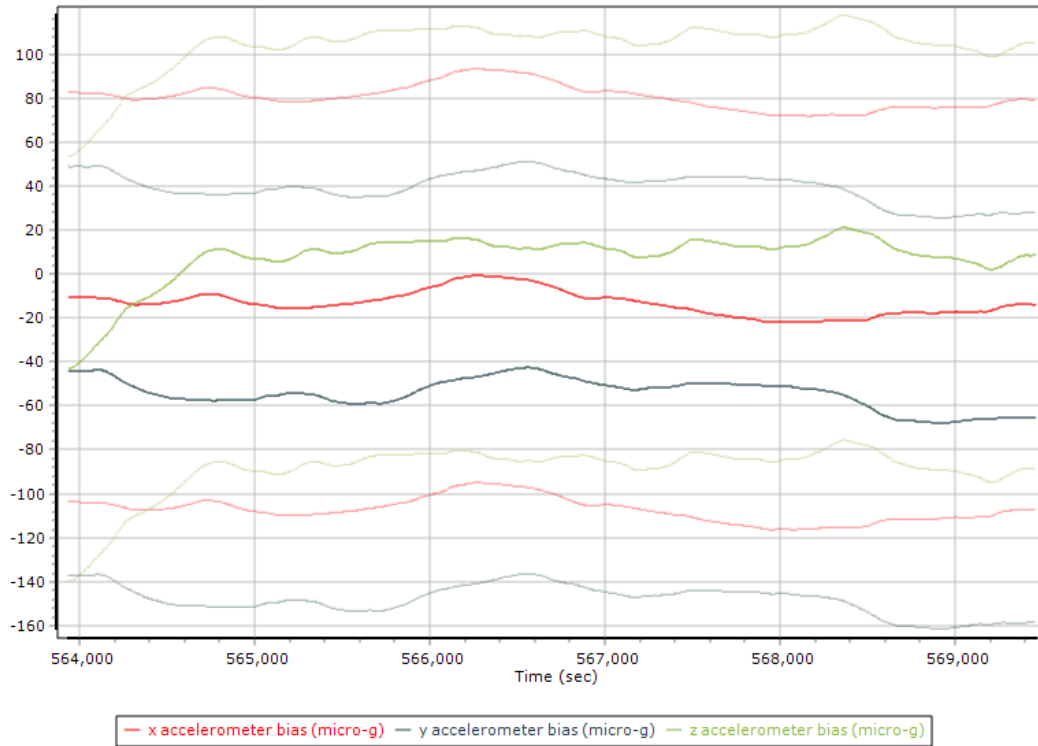


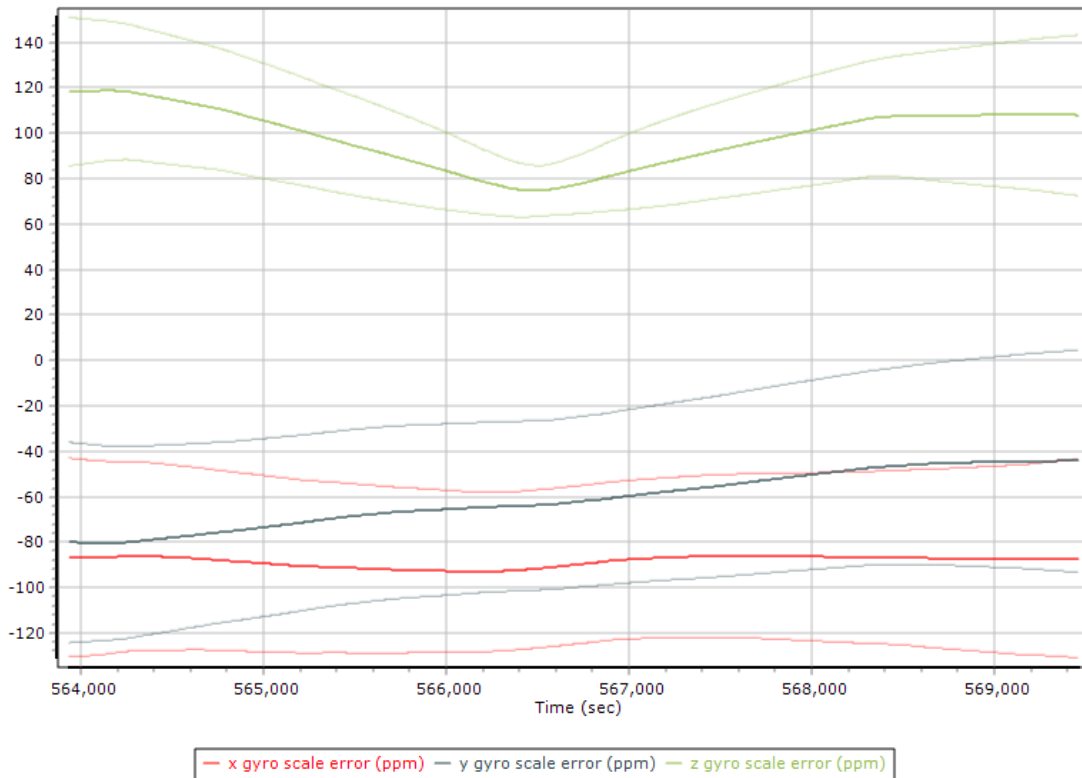
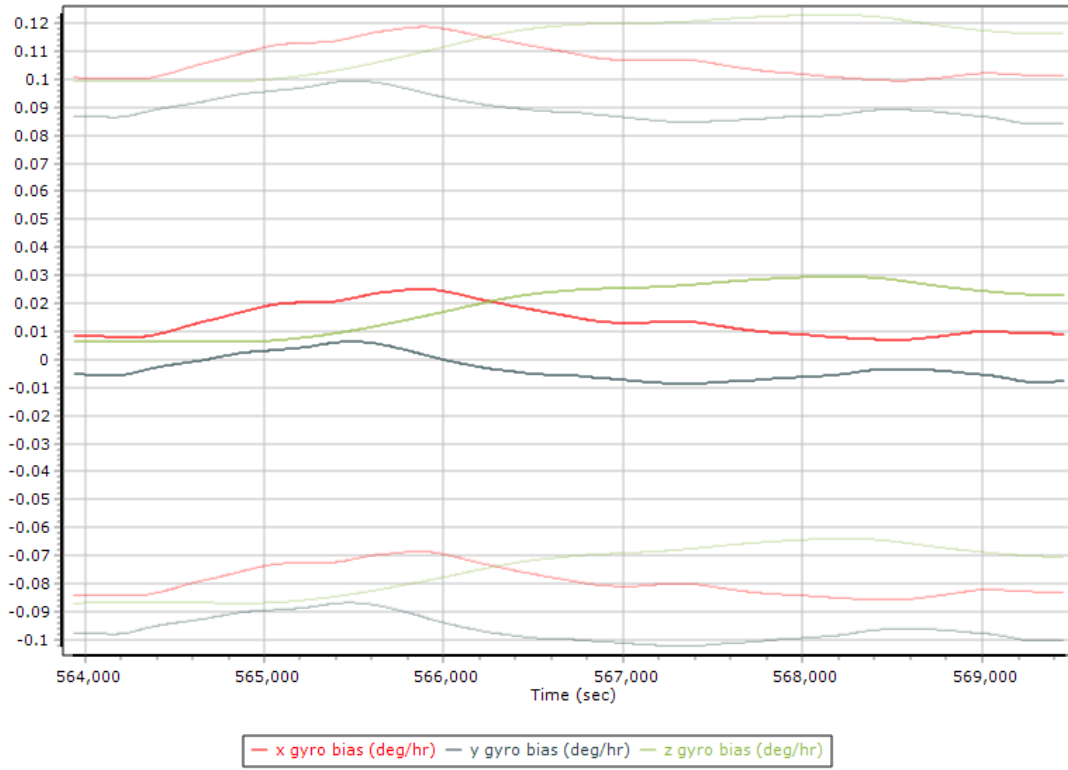
Processing mode



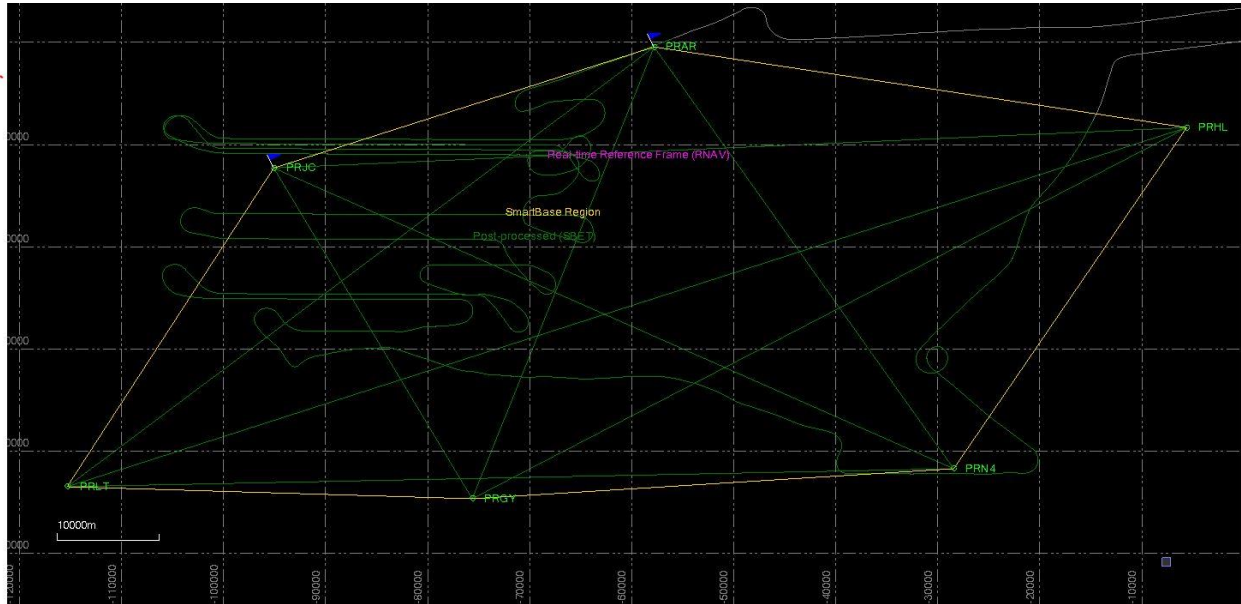
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





RBV18140A



Project Settings

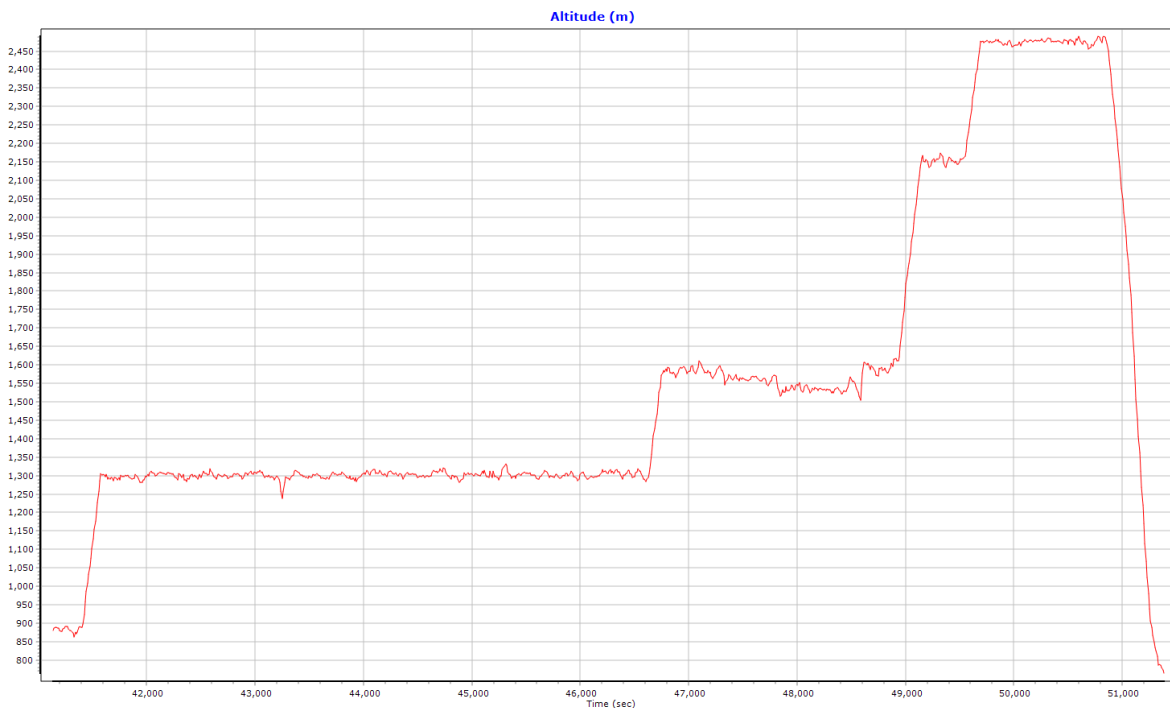
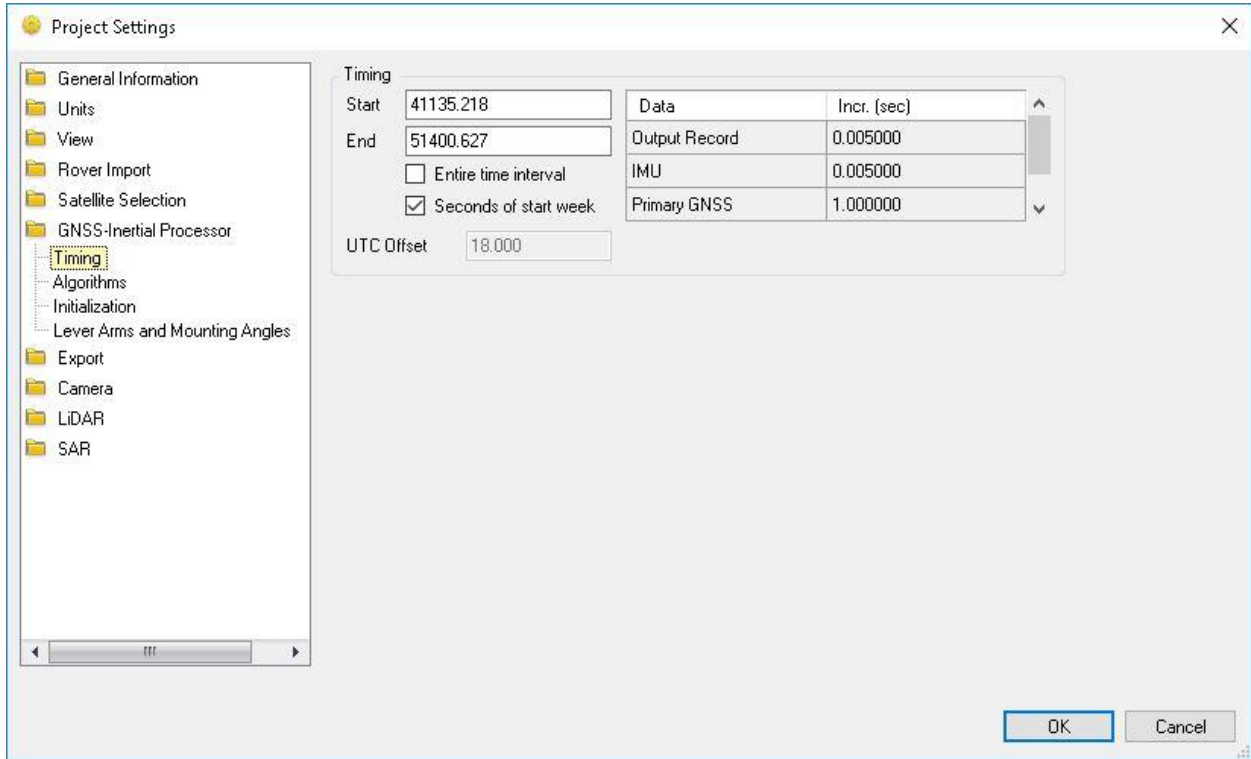
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LIDAR
- SAR

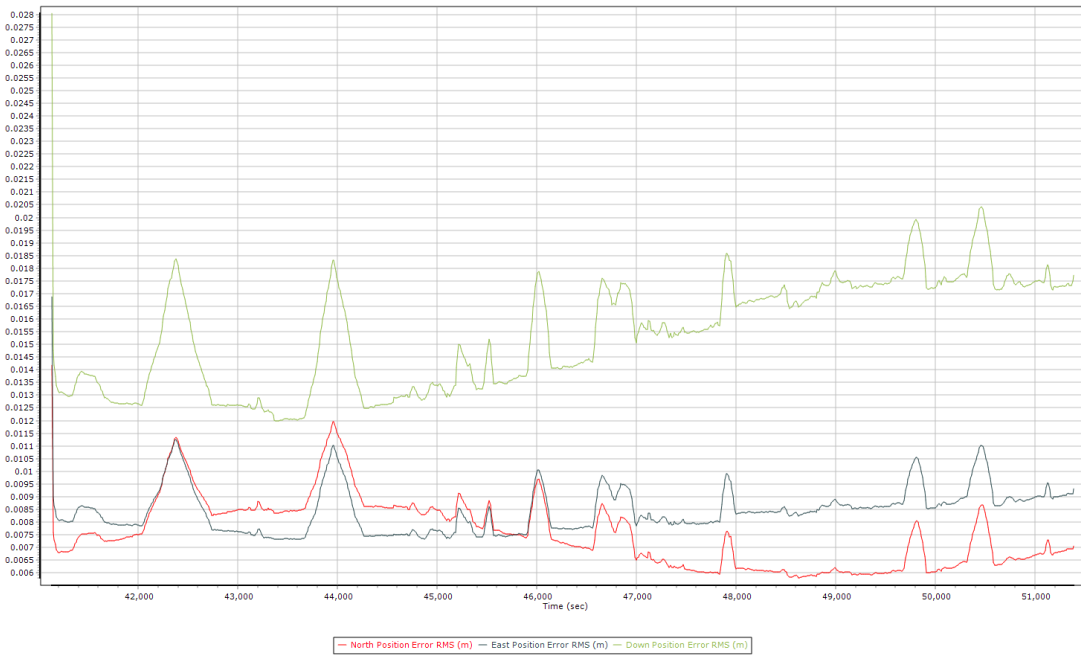
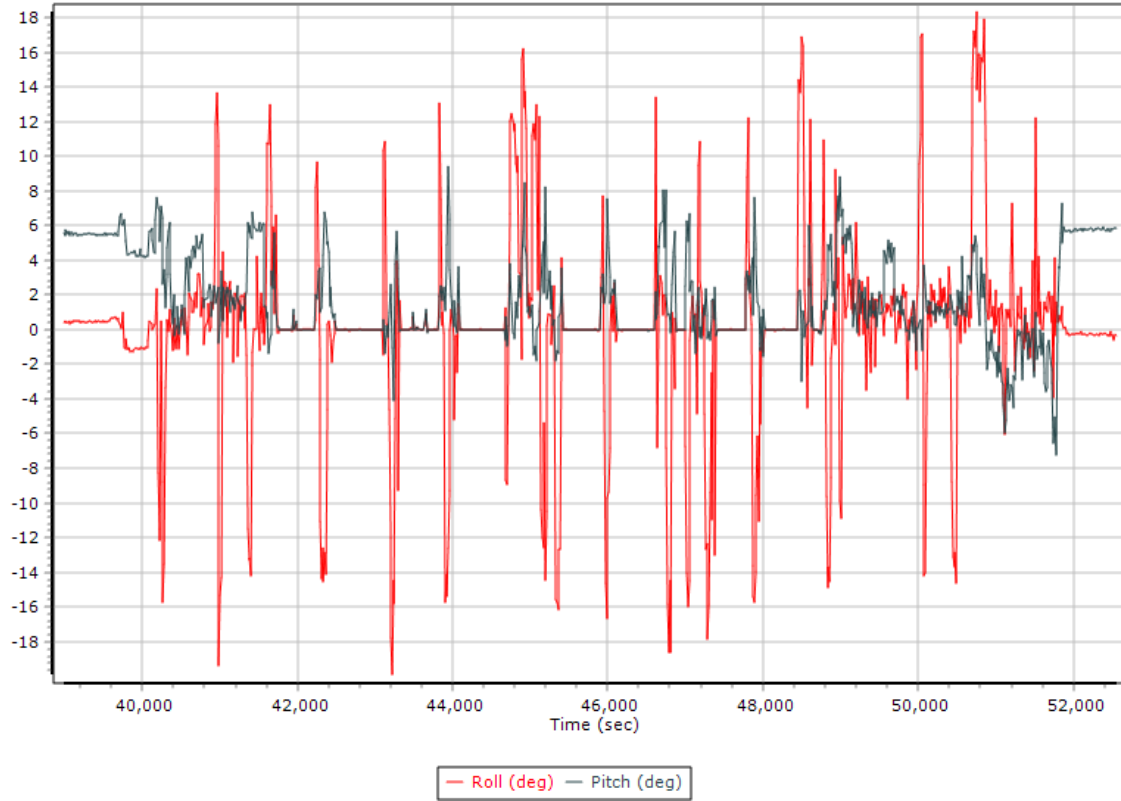
Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.037 m	0.007 m	-0.985 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

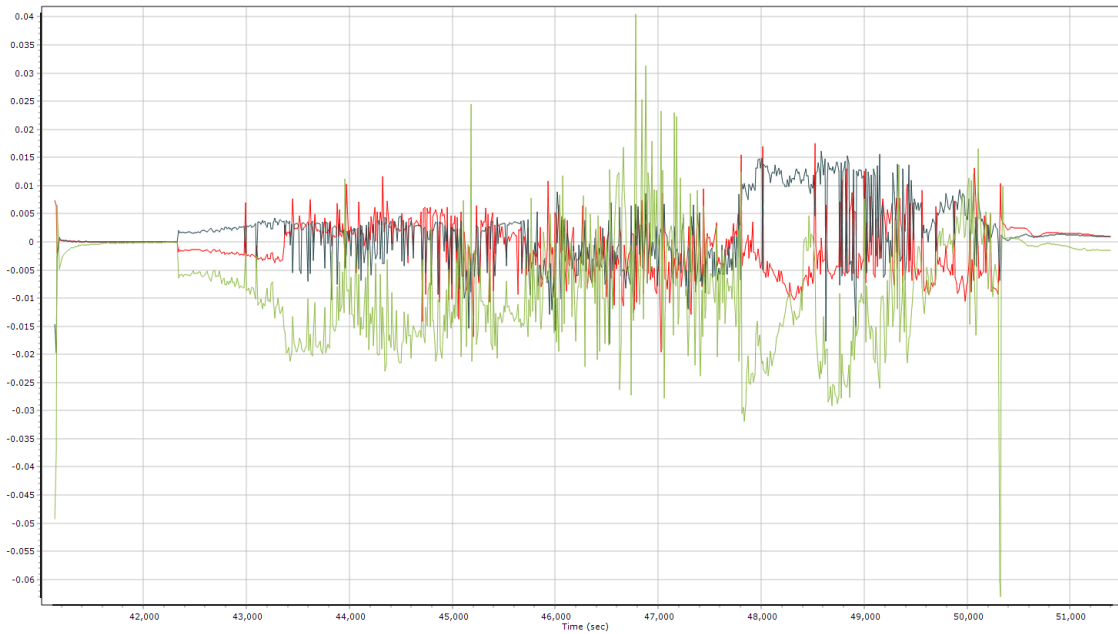
Standard Deviation: <3cm 10cm 50cm 1m 10m

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

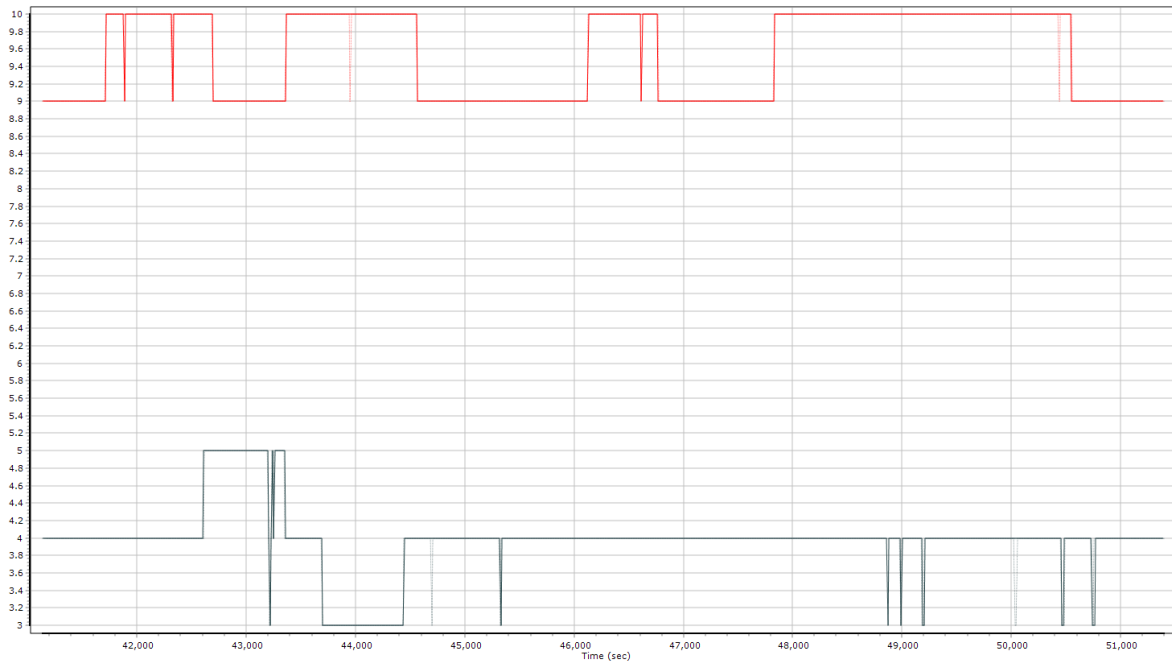
OK Cancel



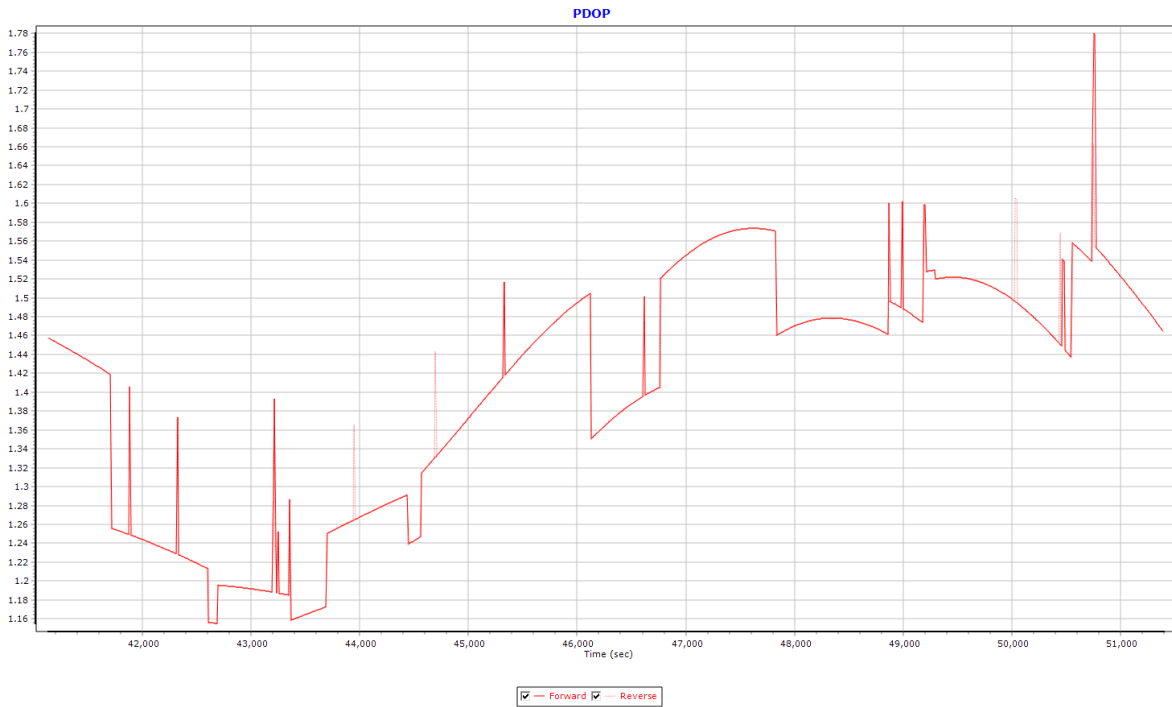
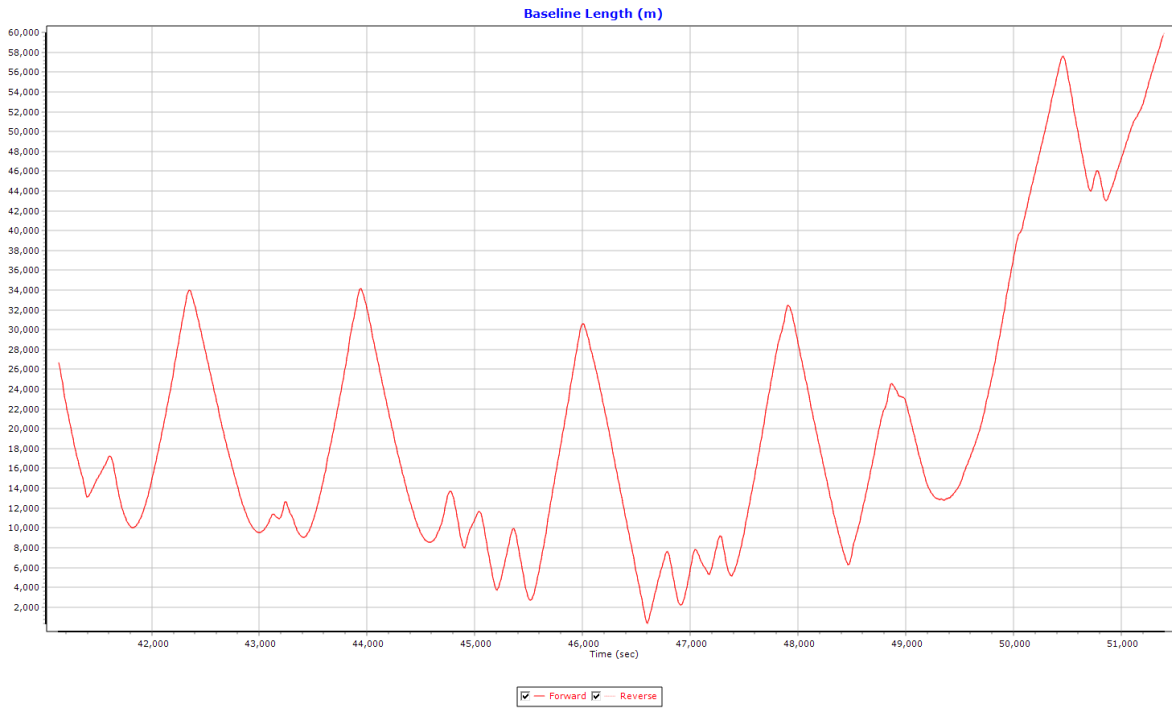


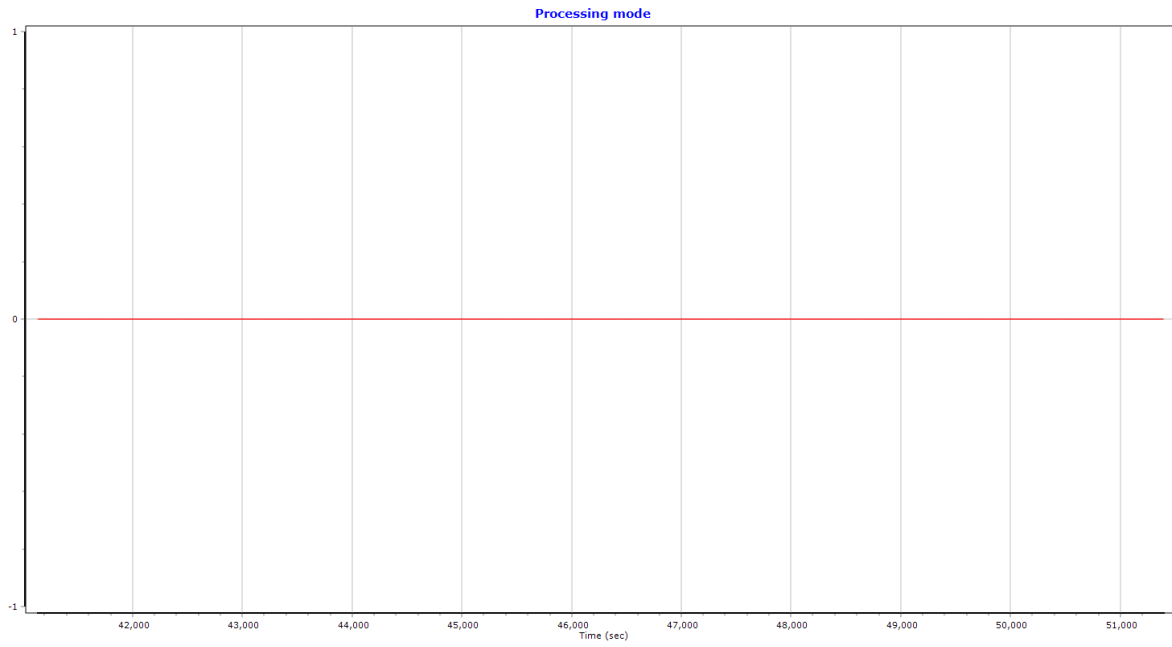


— North (m) — East (m) — Down (m) — DR mode



— Number of GPS Satellites — Number of GLONASS Satellites

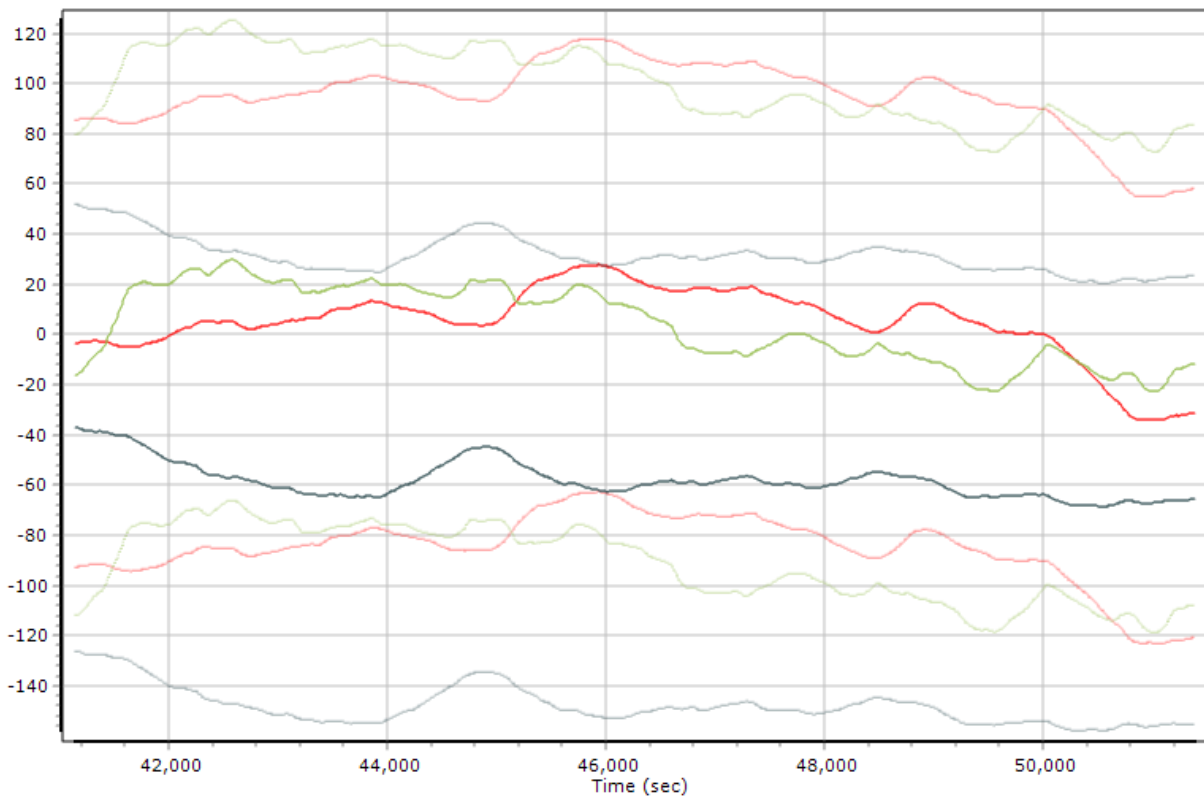




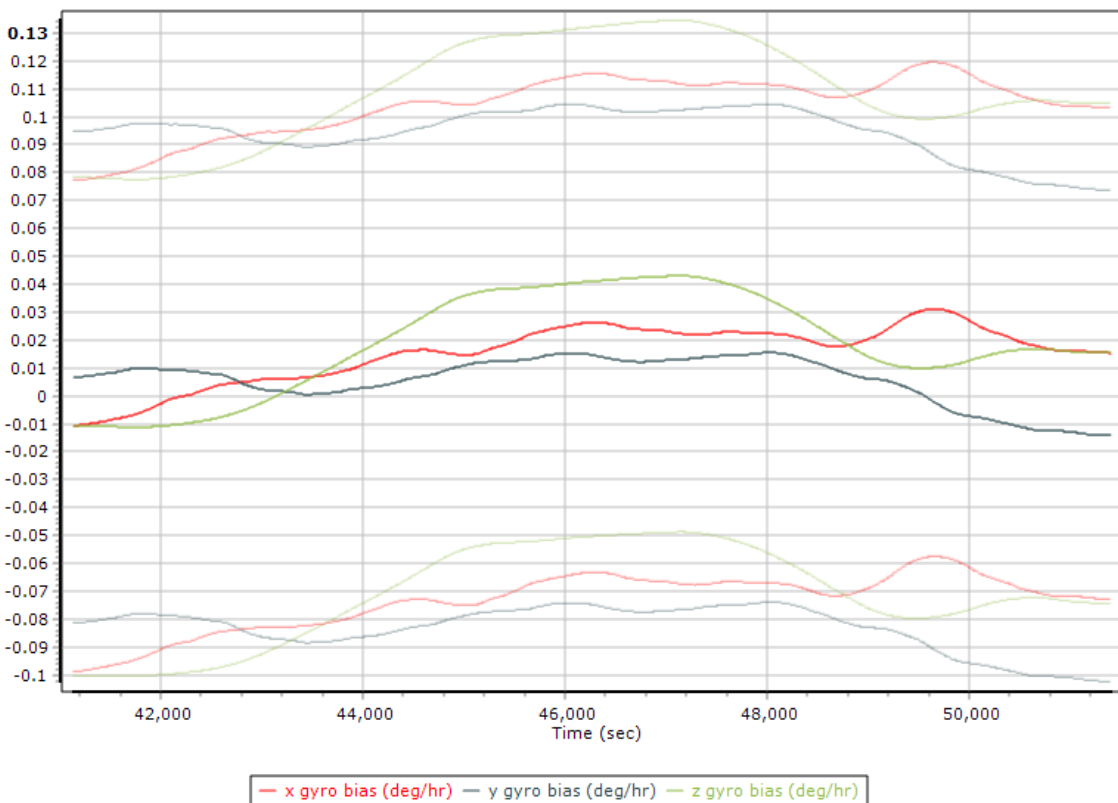
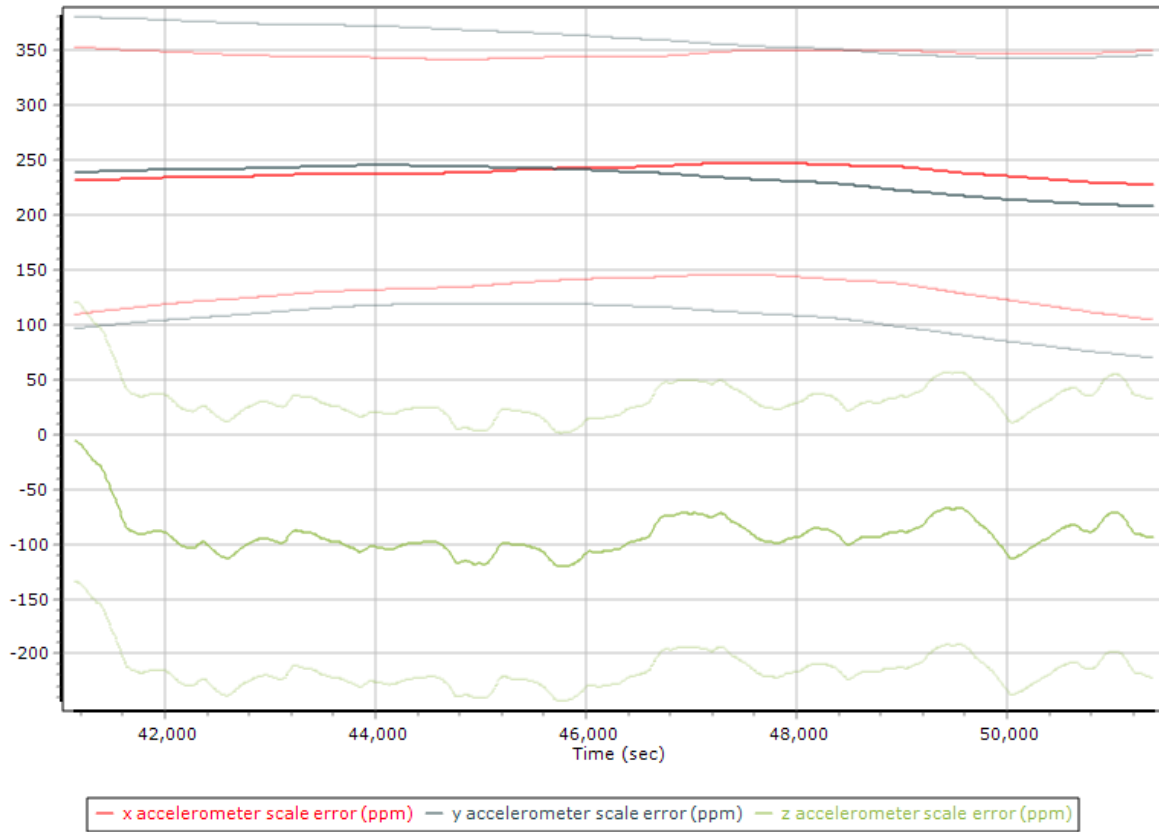
Forward Reverse

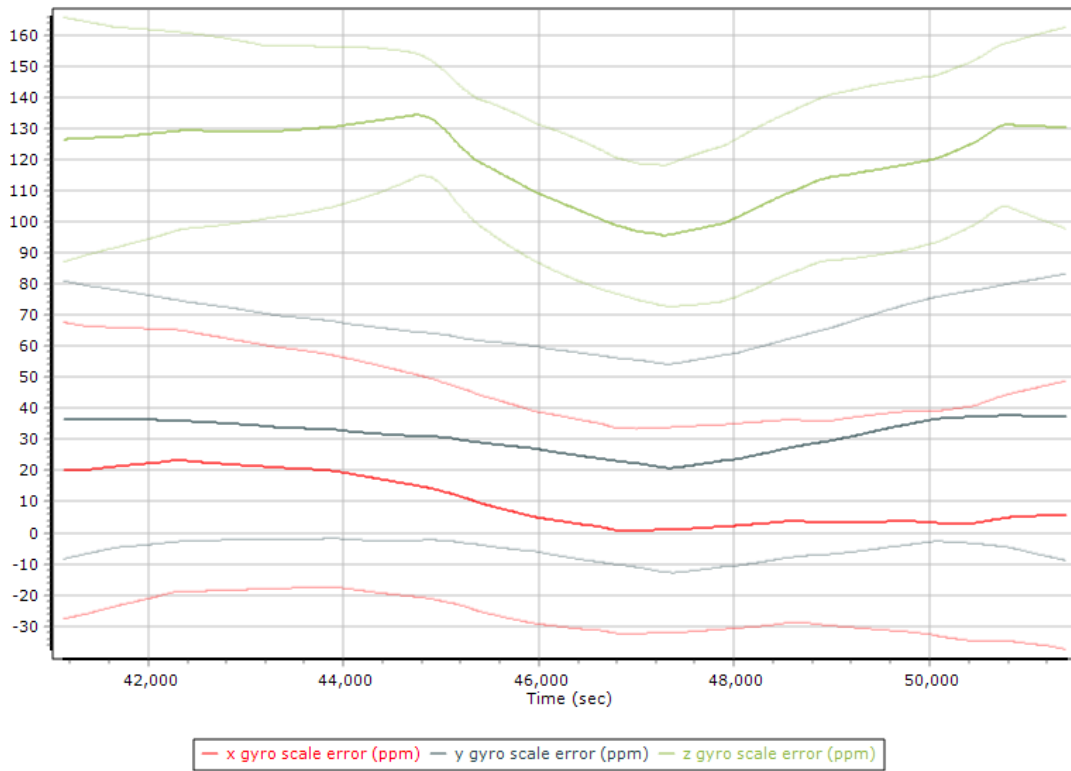
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

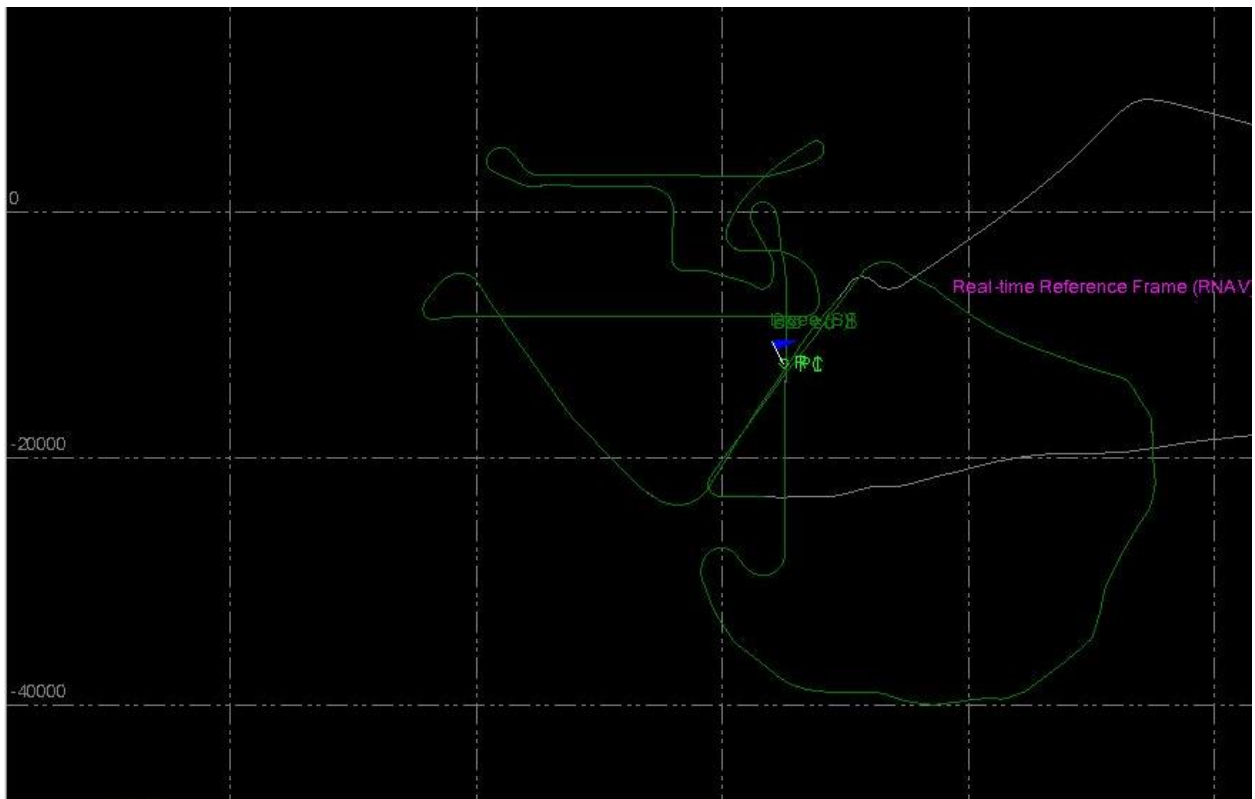


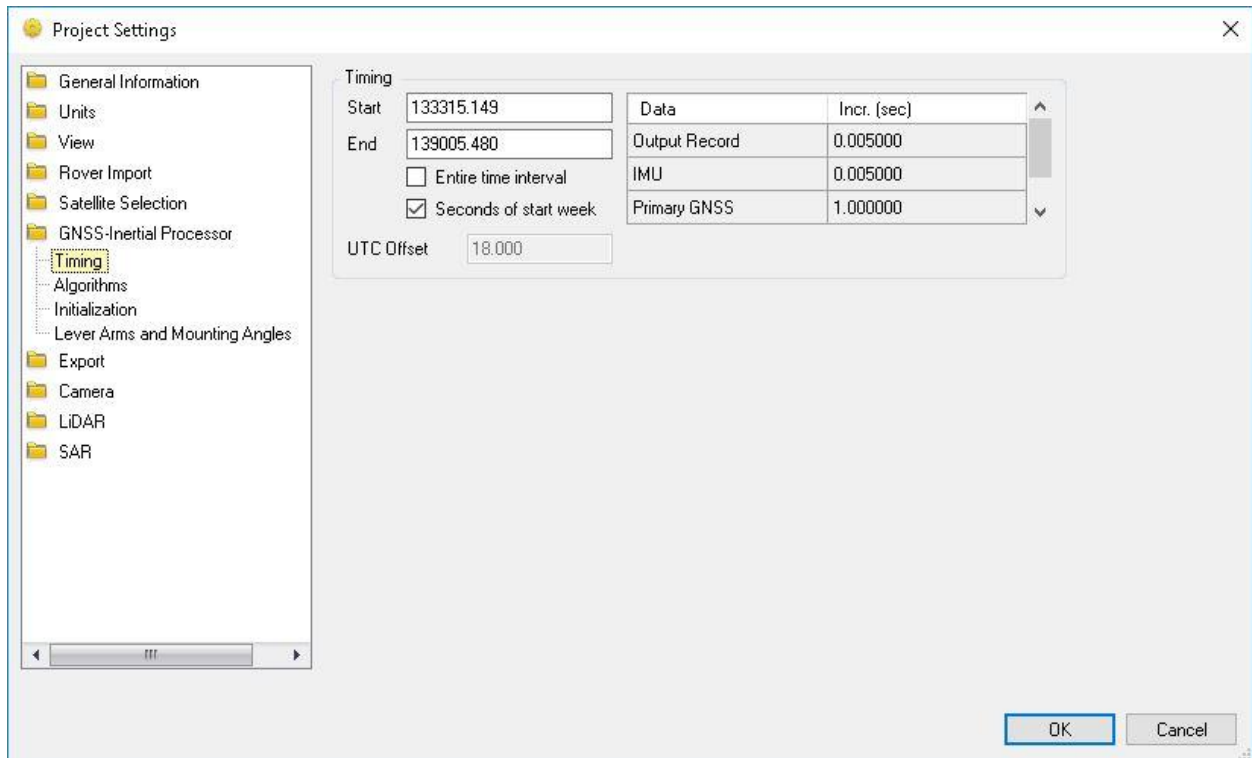
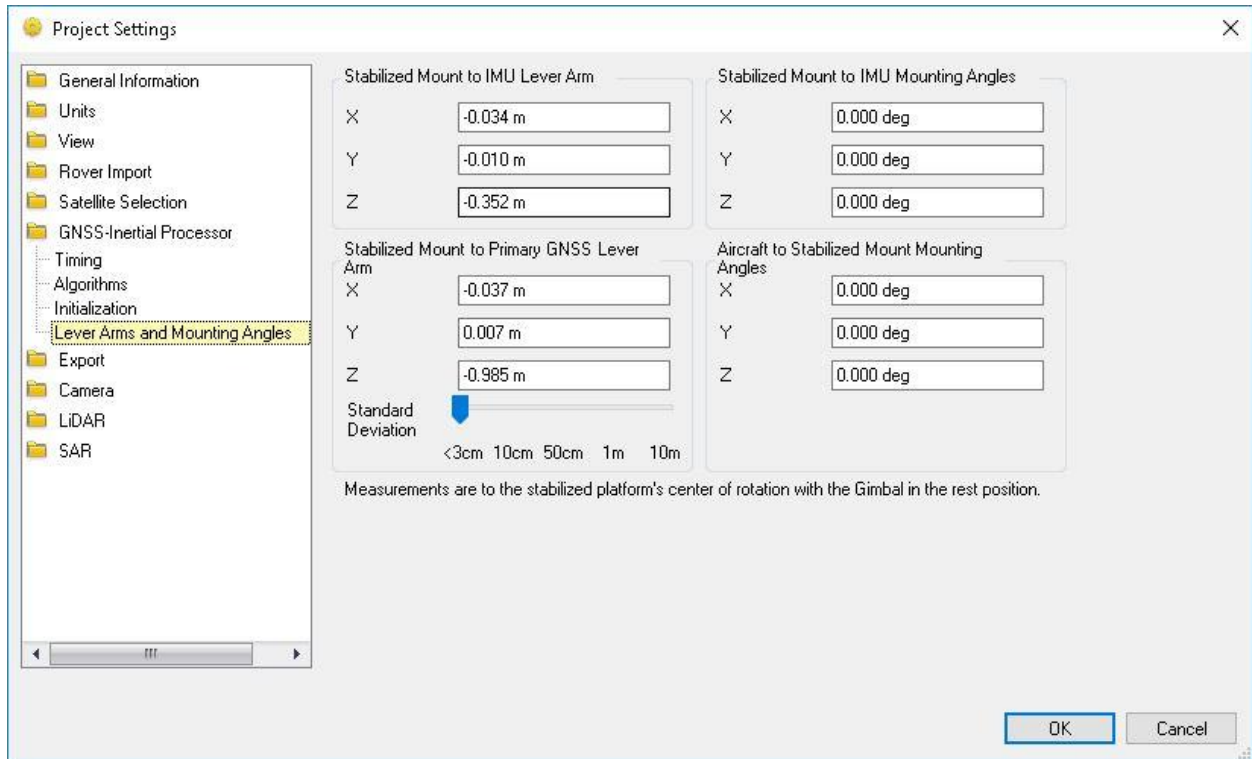
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)

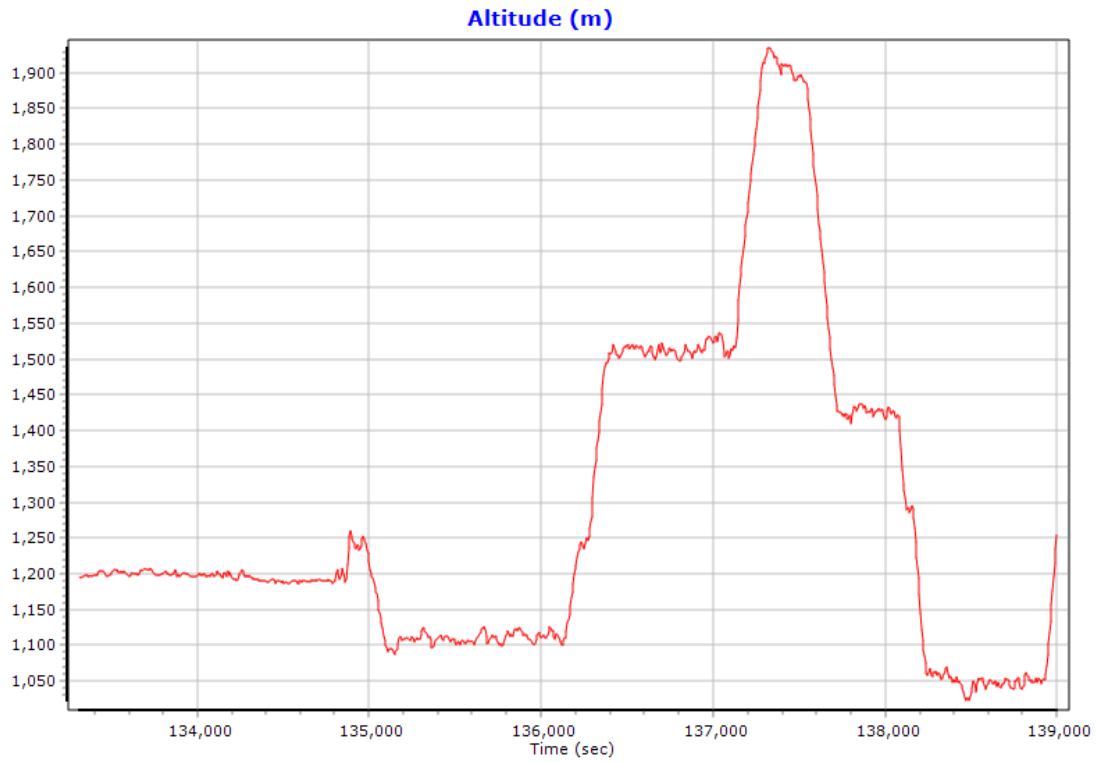


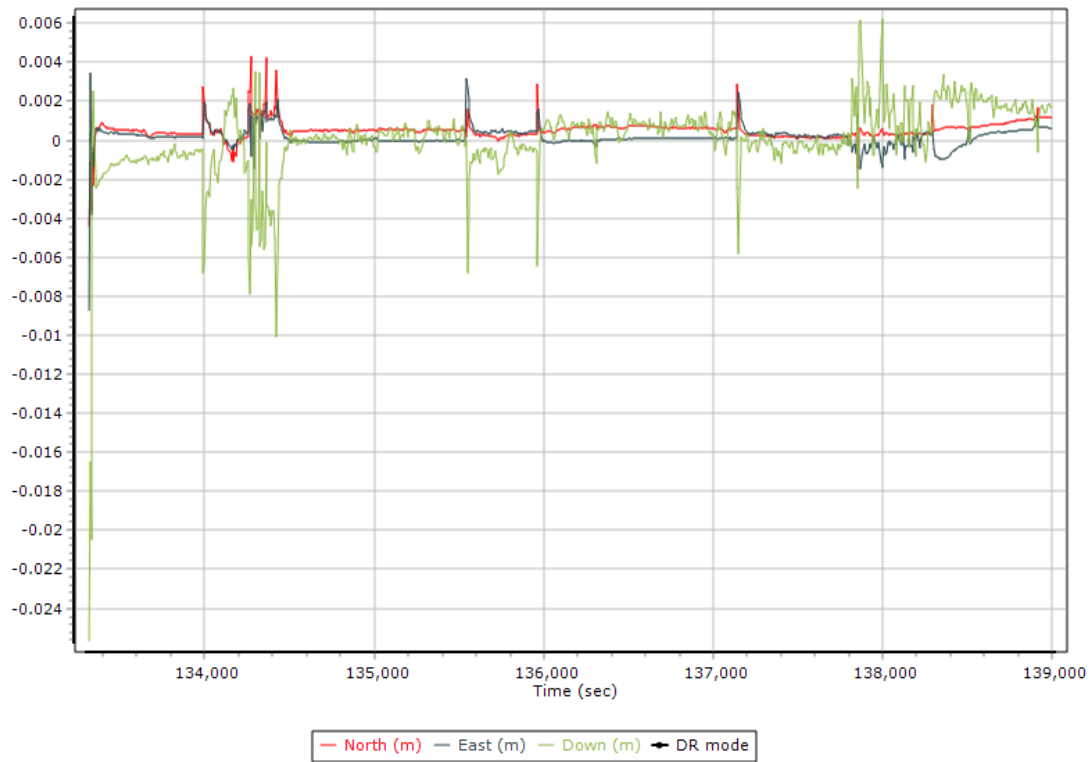
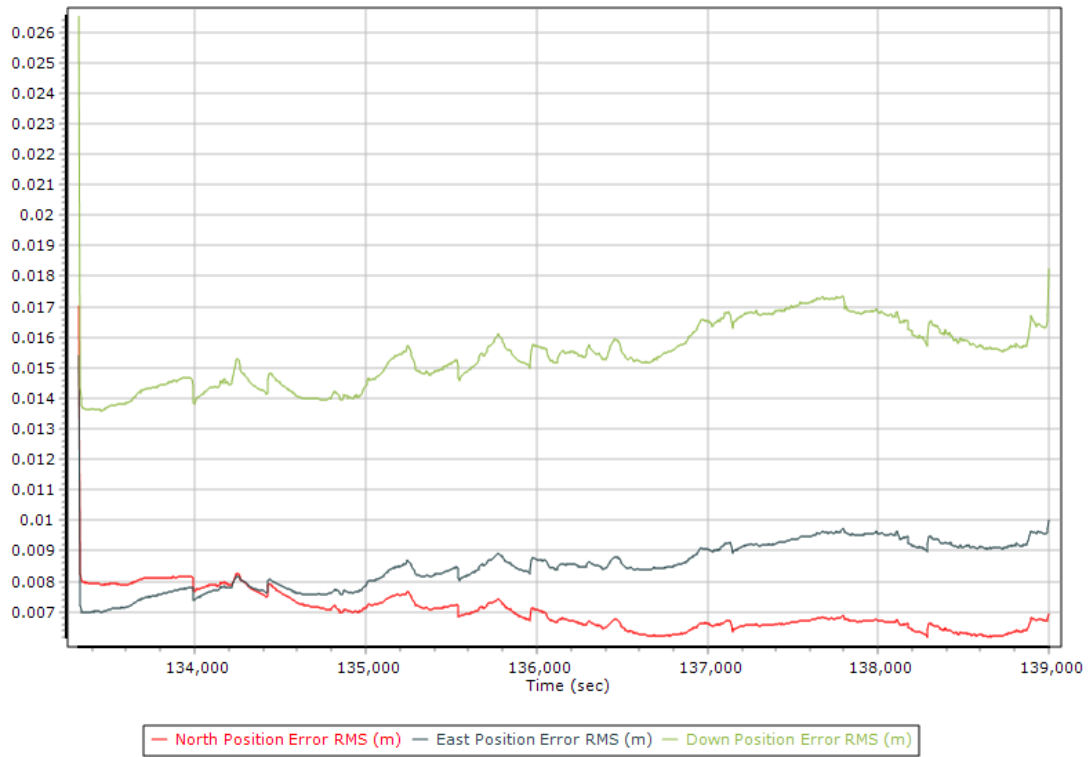


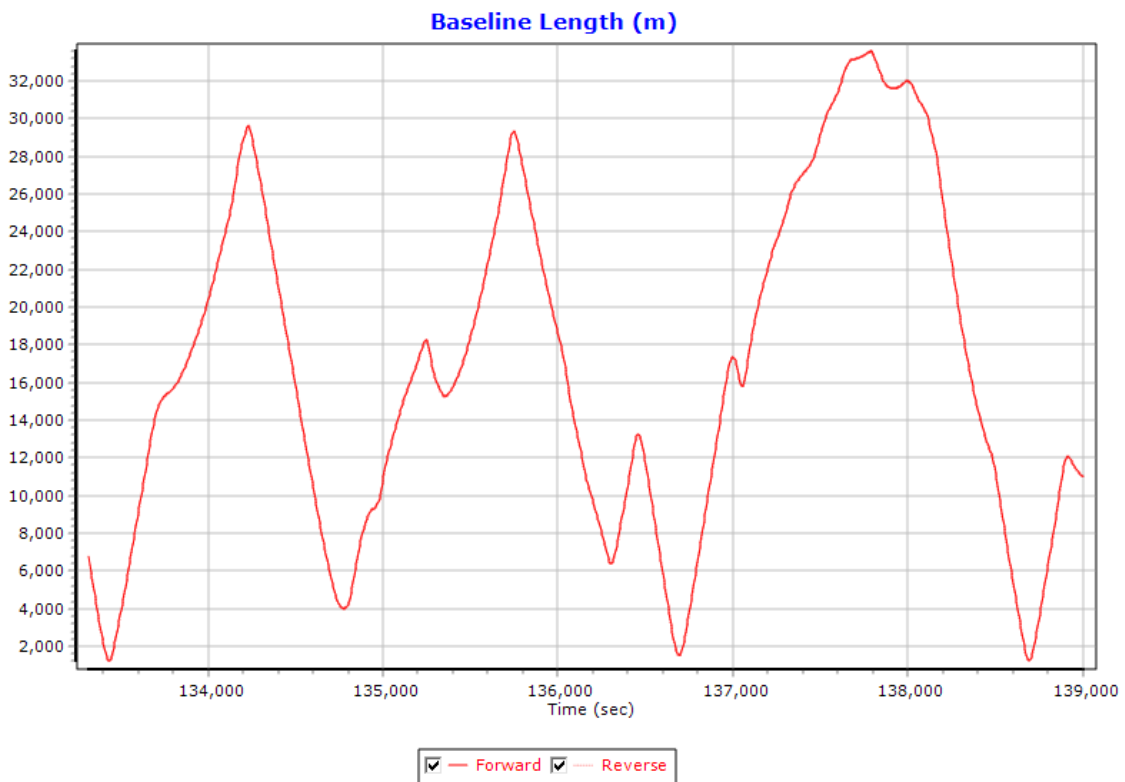
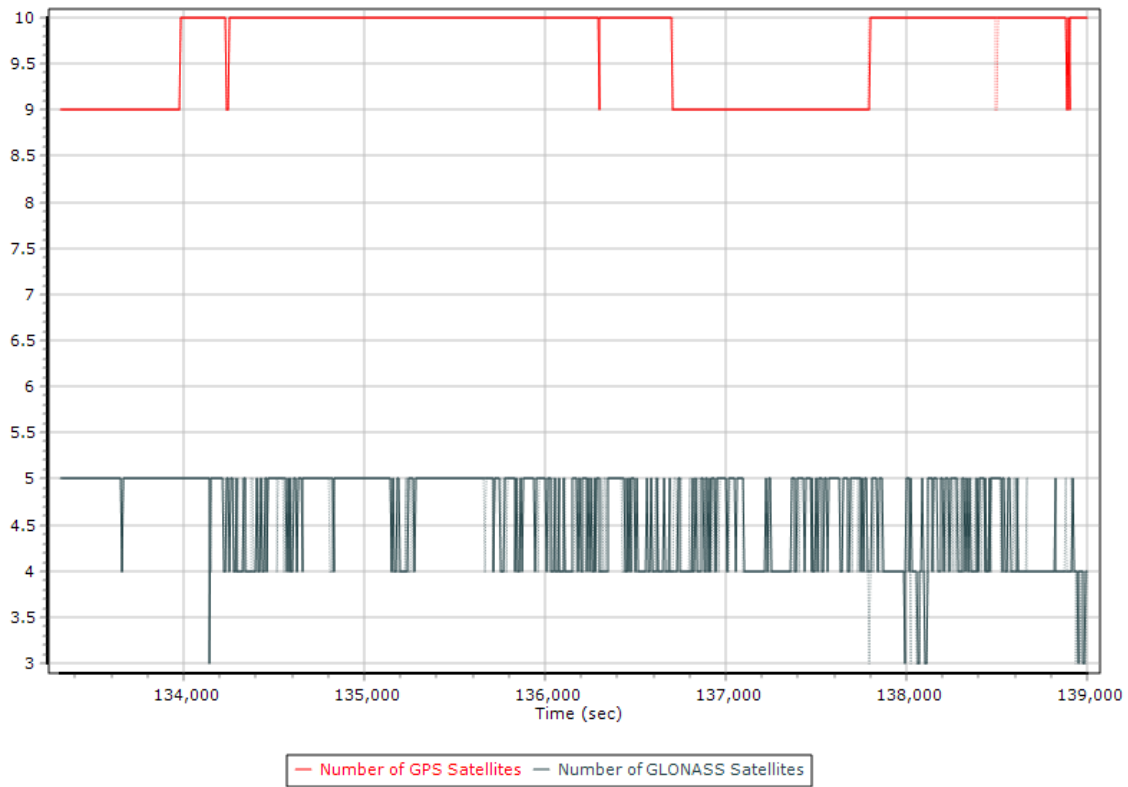
RBV18141A

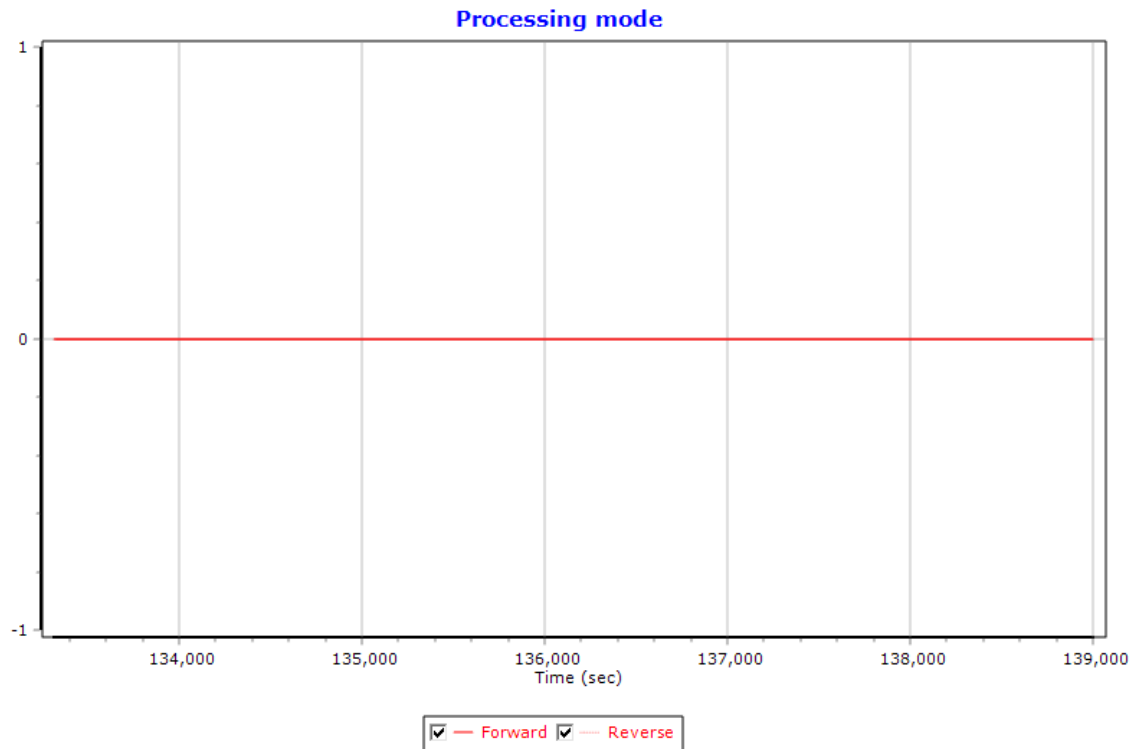
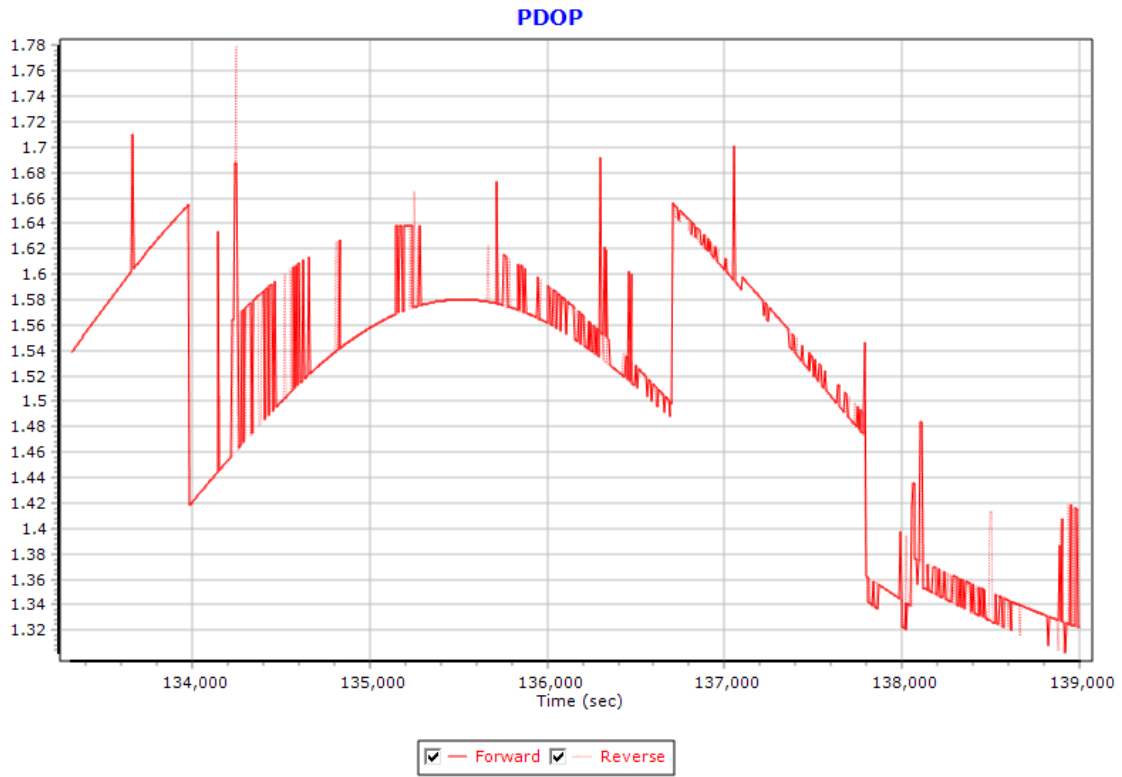






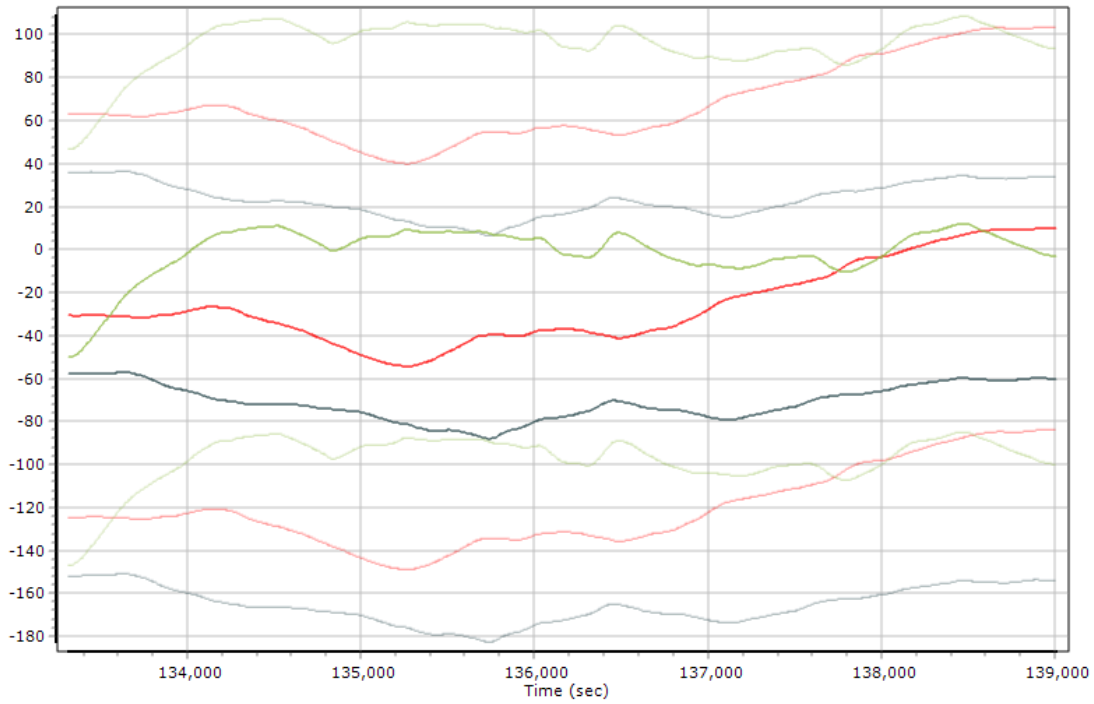




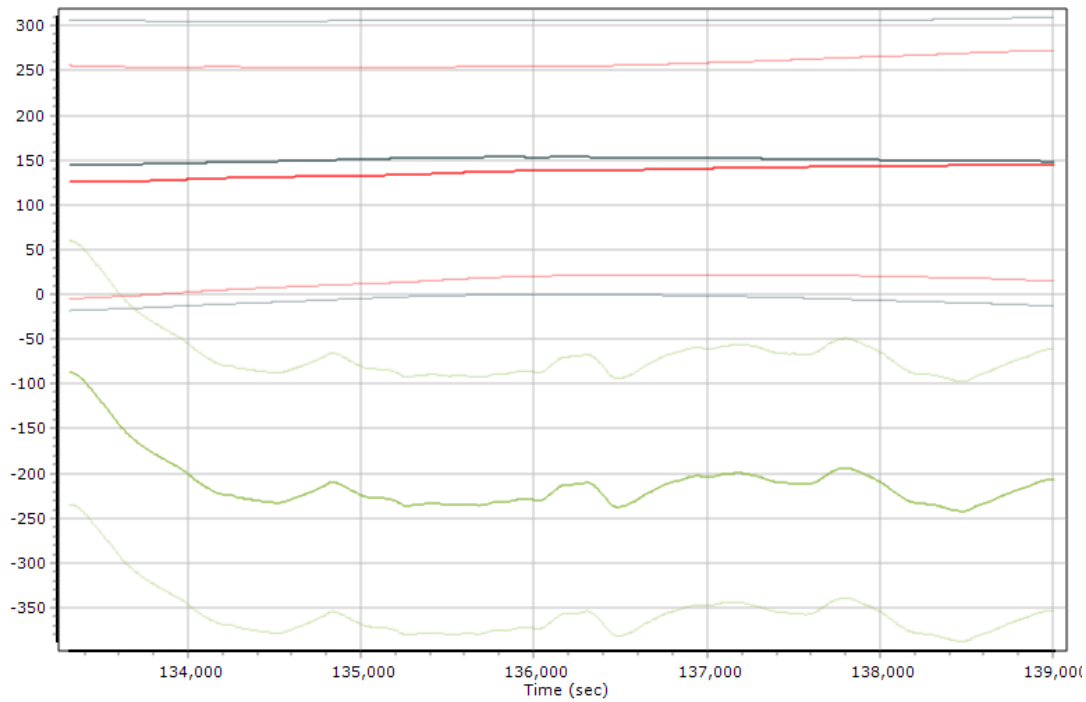


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

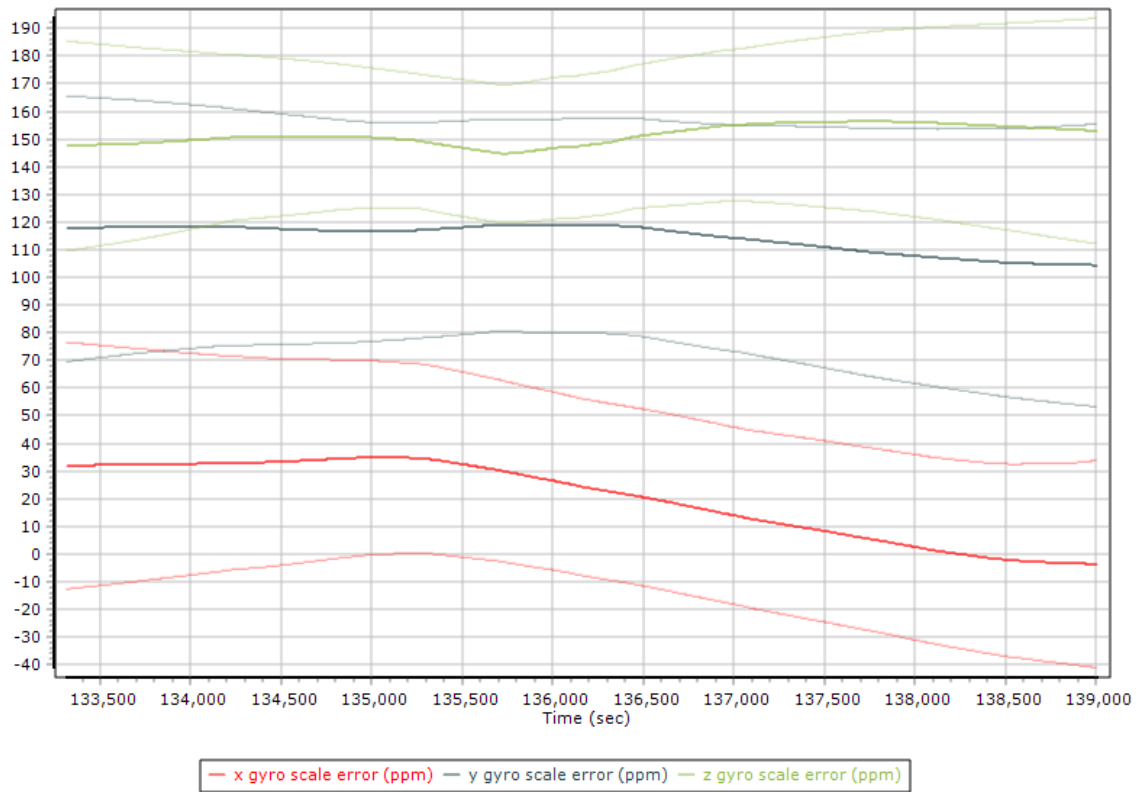
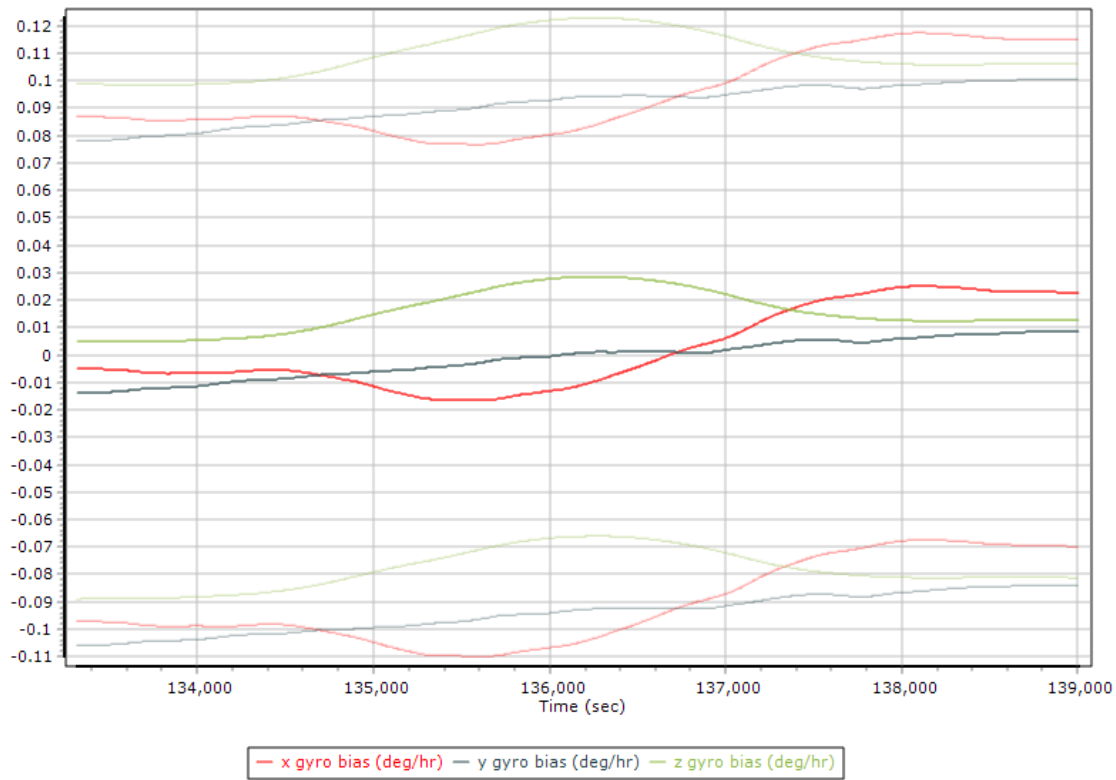
Sensor Errors



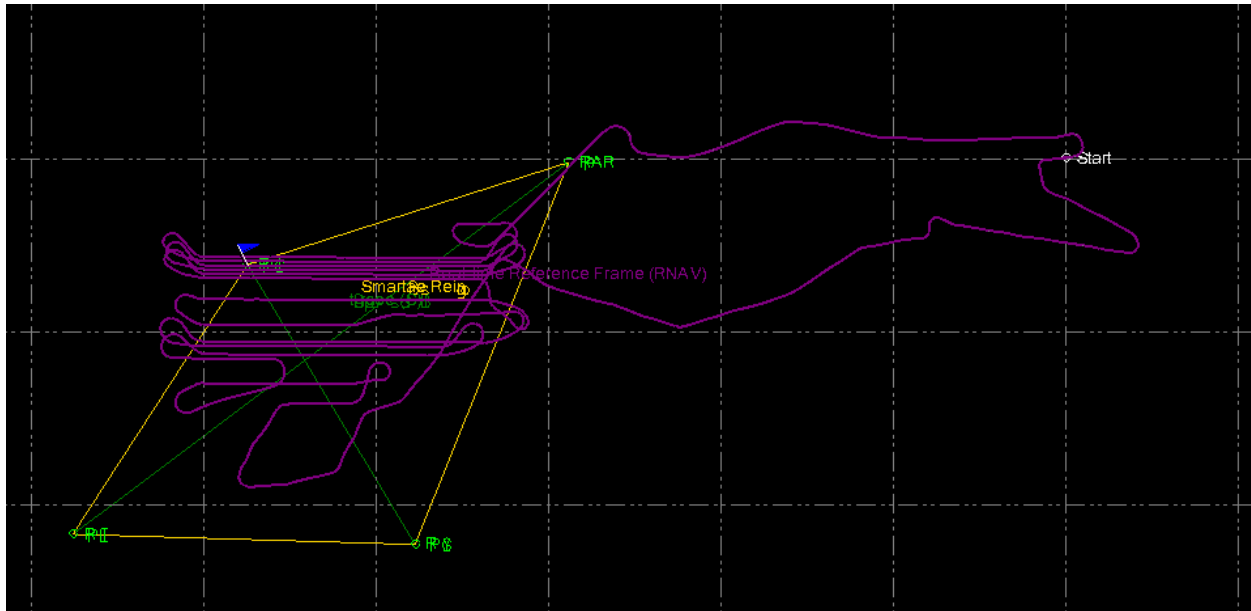
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



RBV18142A



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: -0.037 m	X: 0.000 deg
Y: 0.007 m	Y: 0.000 deg
Z: -0.985 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.

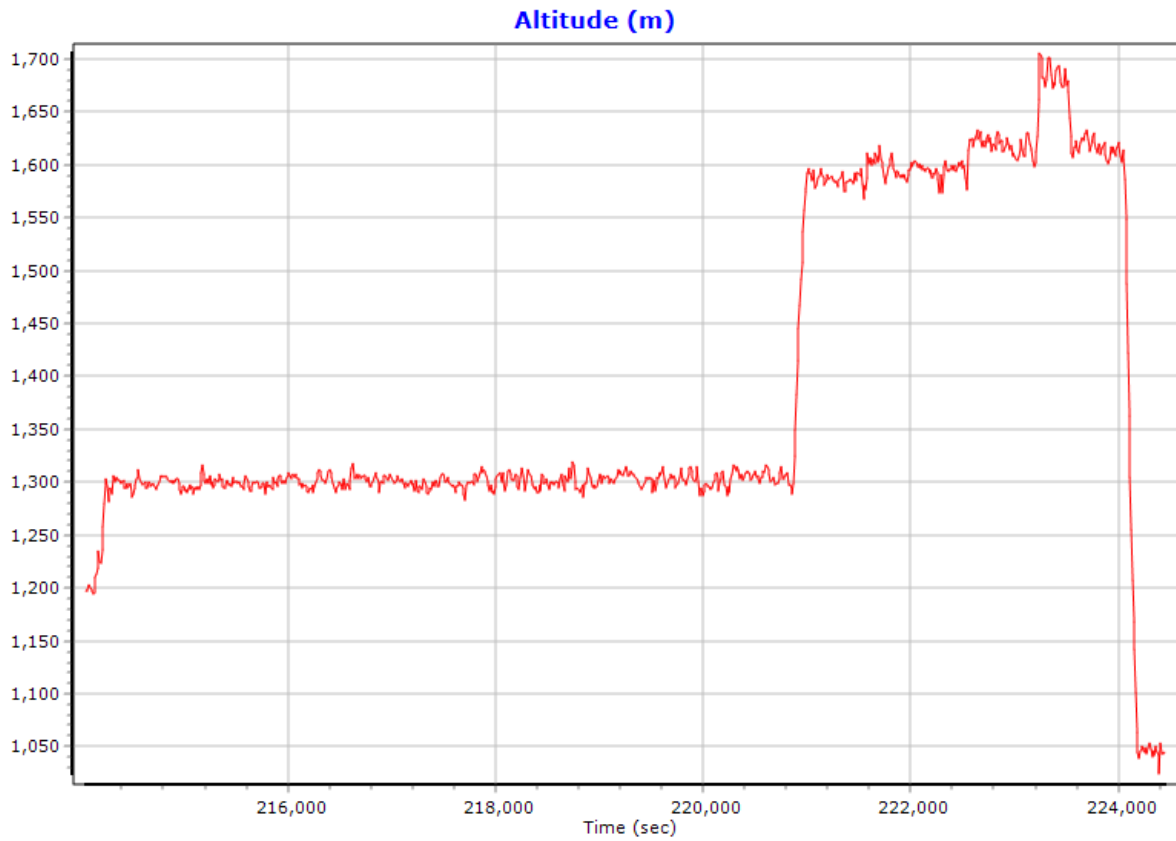
OK Cancel

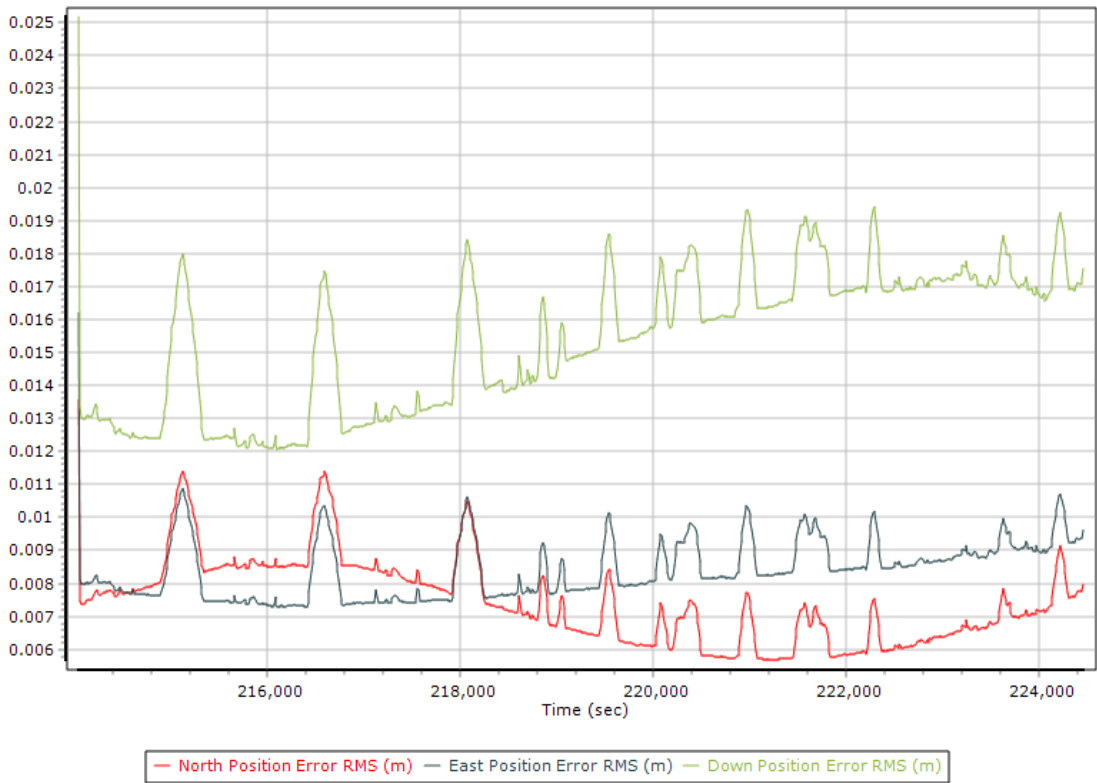
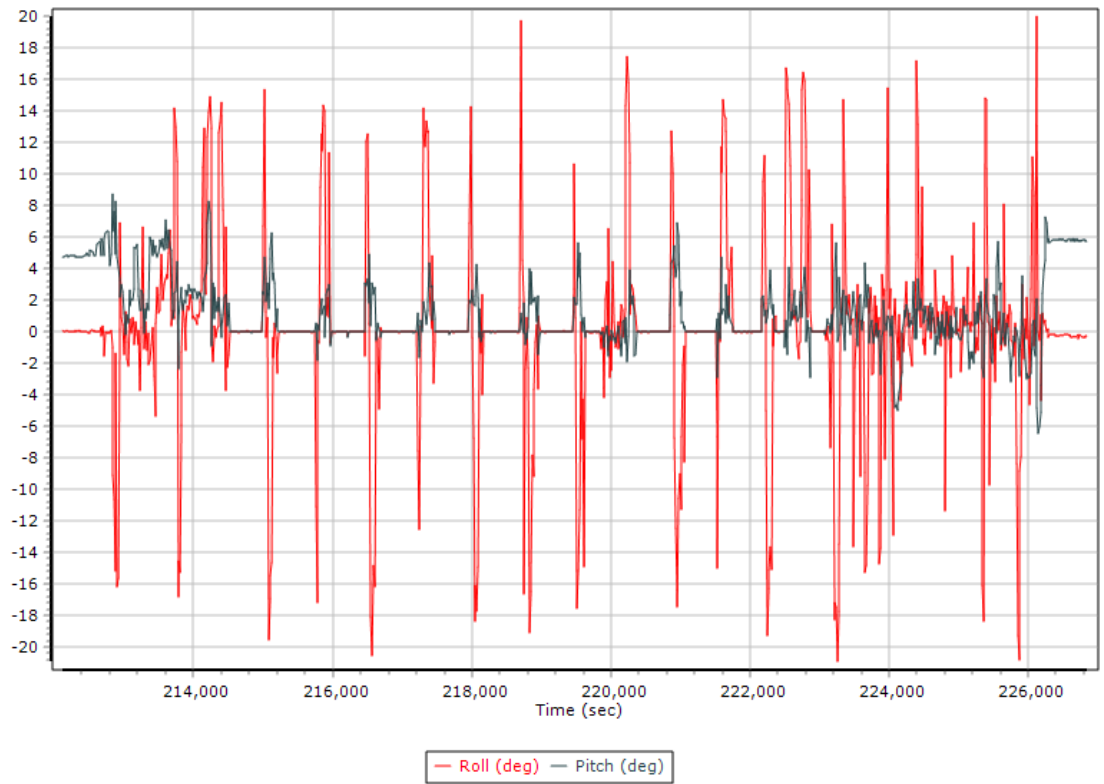
Project Settings

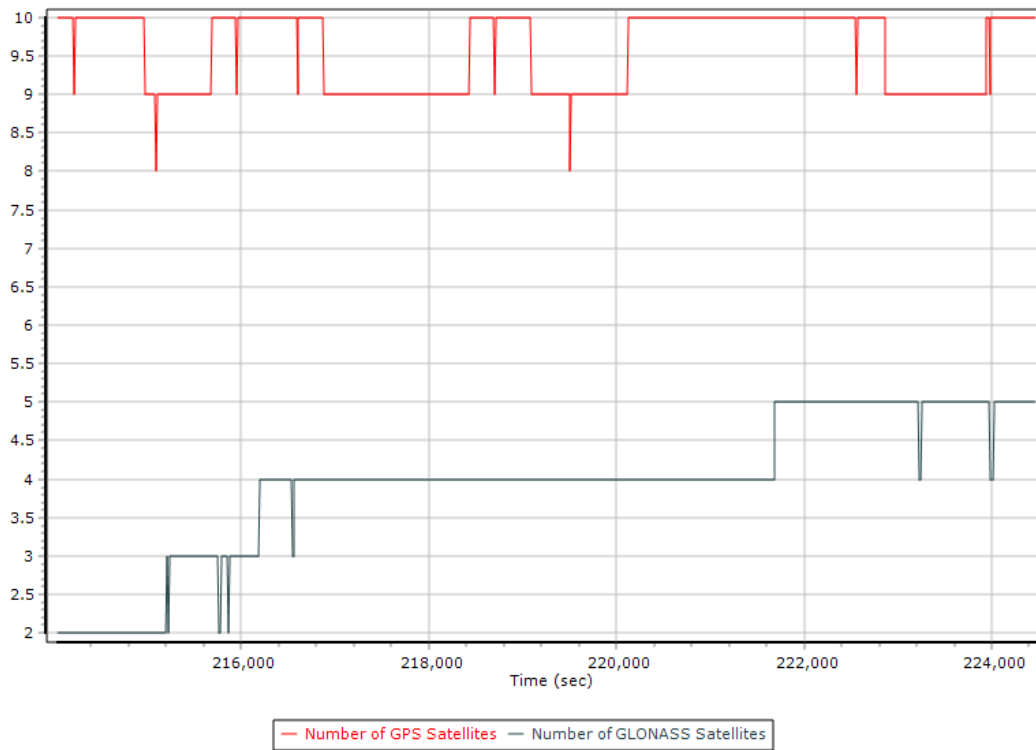
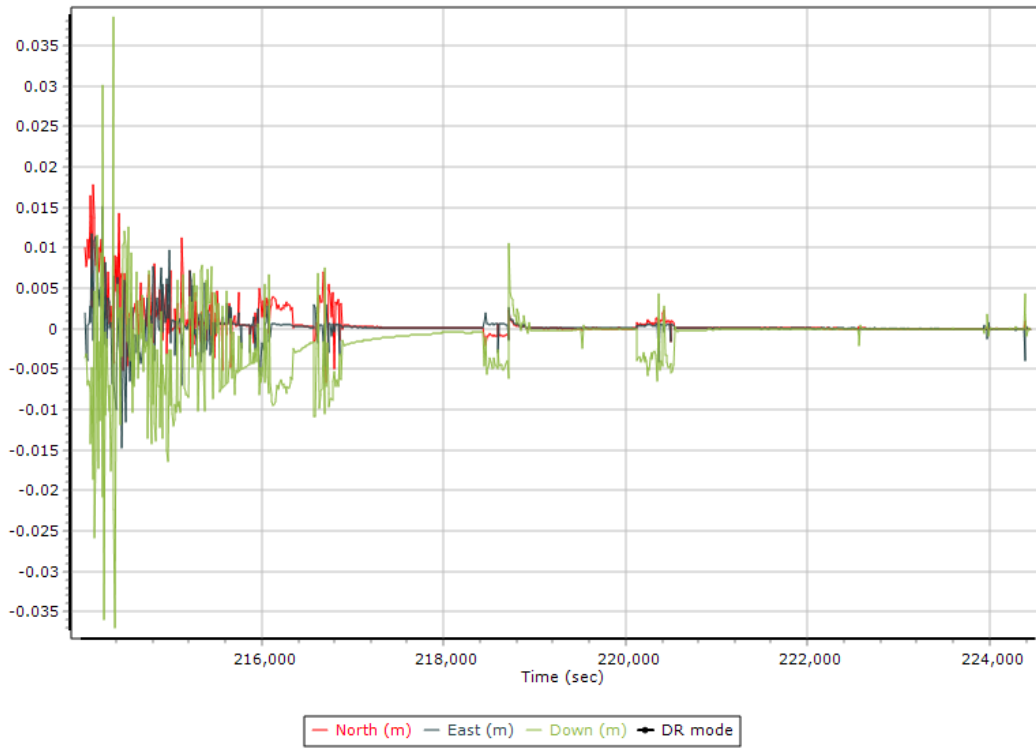
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
Timing

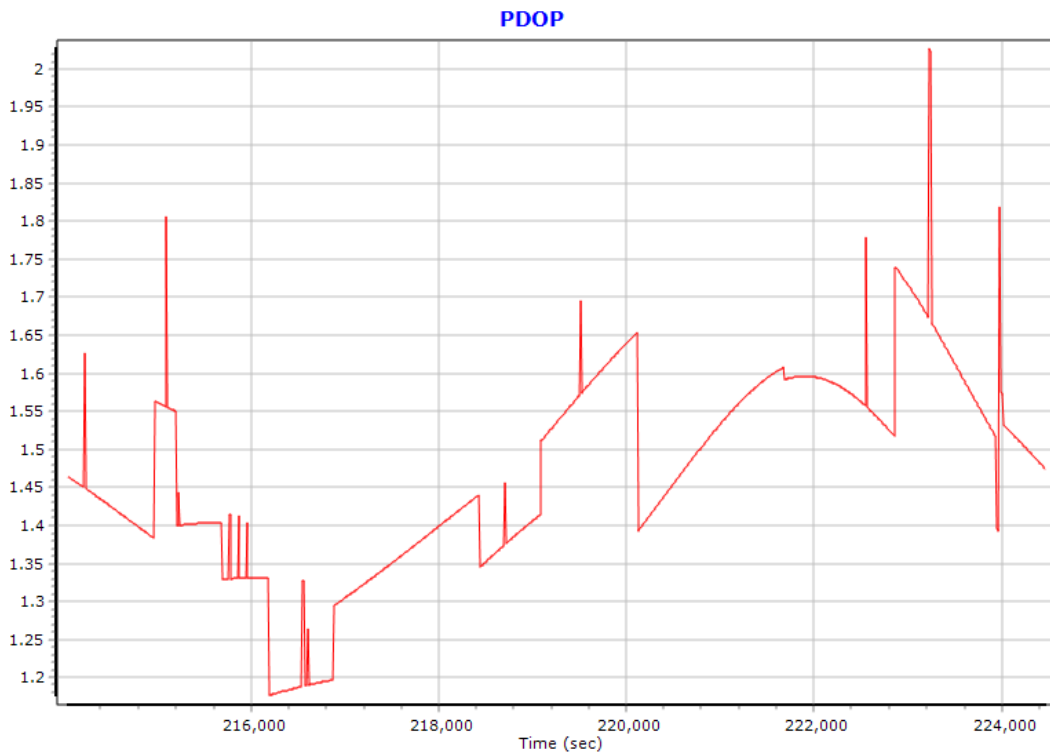
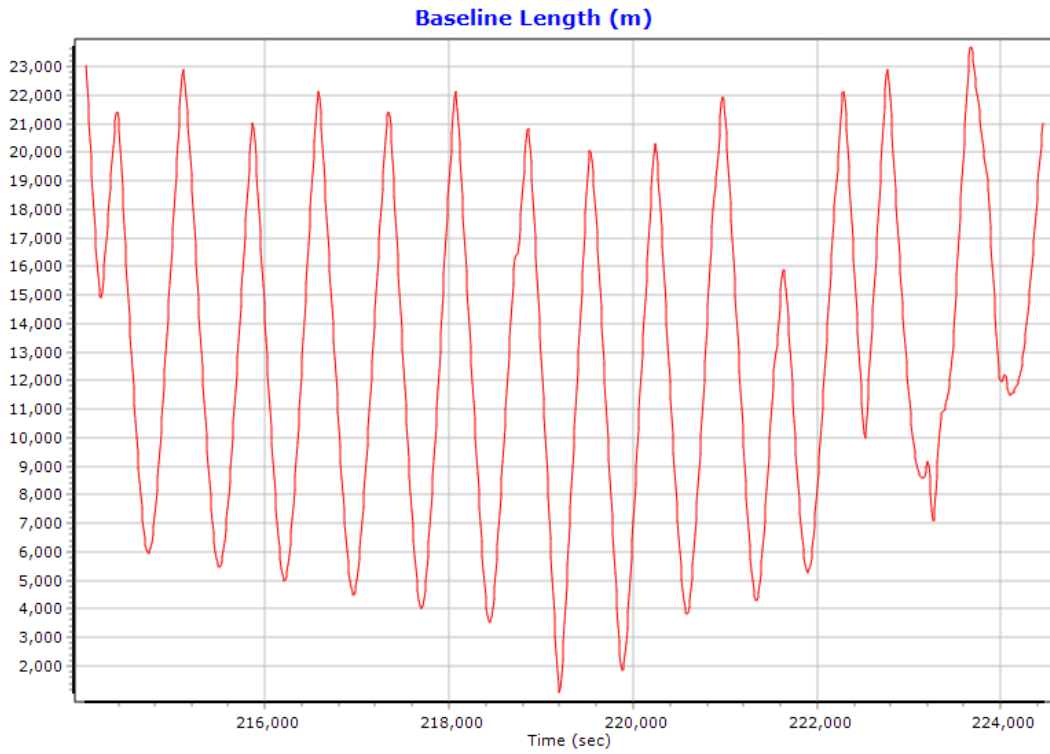
Timing
Start: 214050.073
End: 224468.517
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

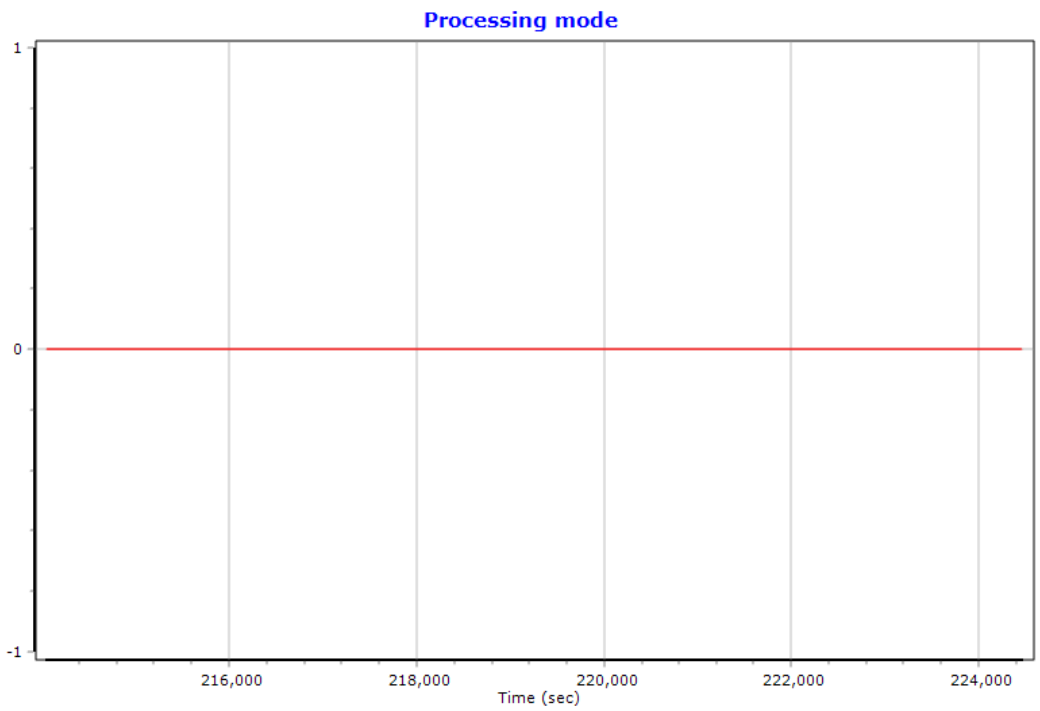
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000





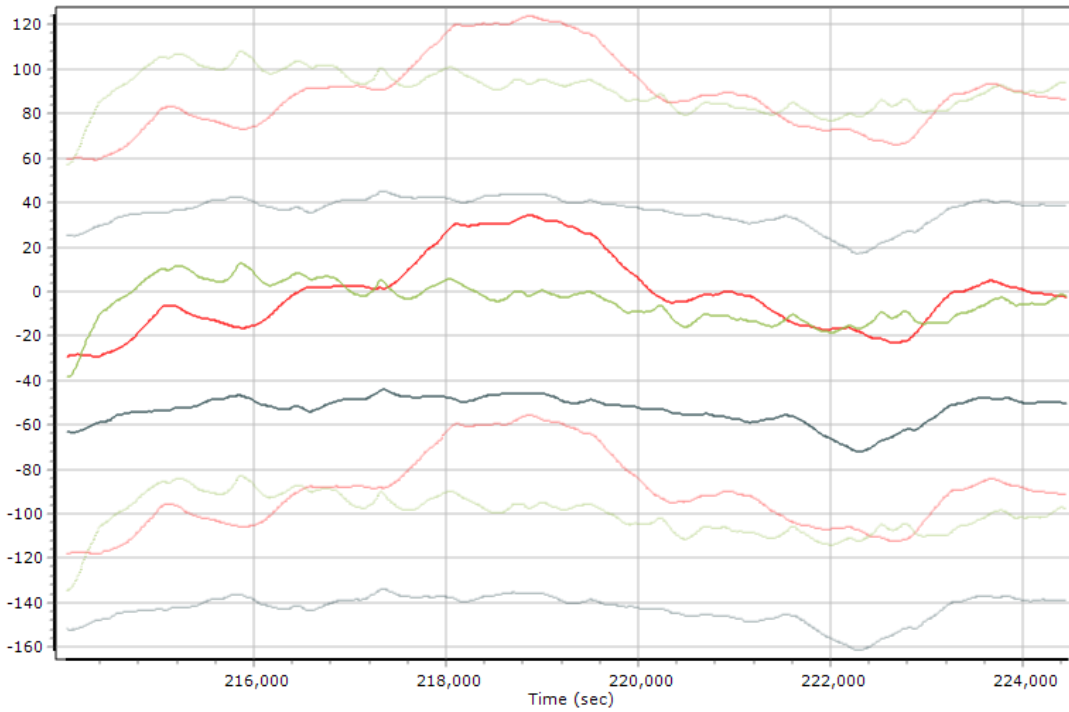




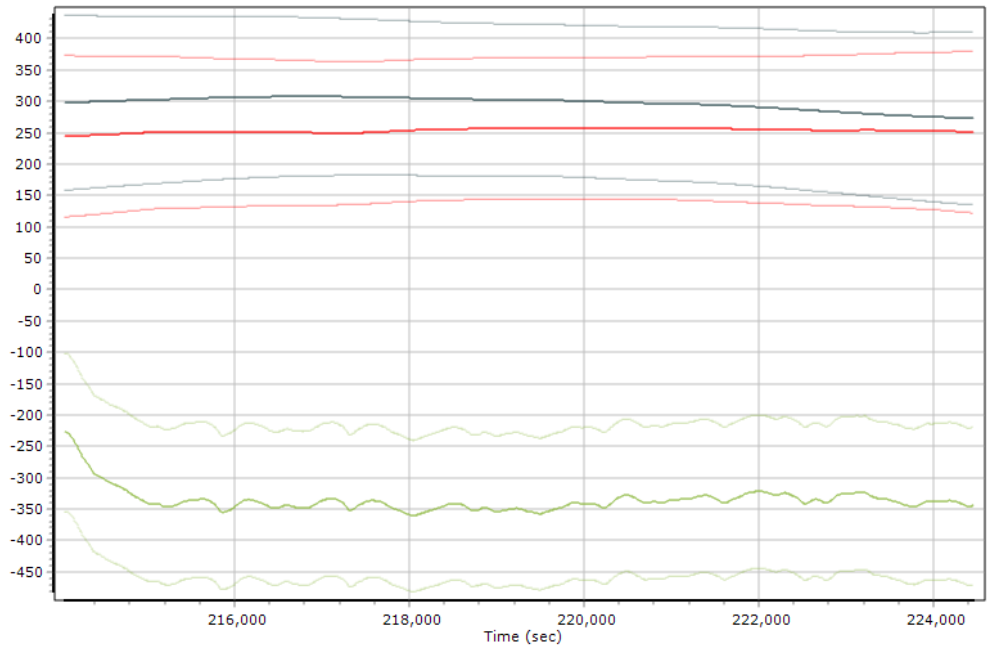


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

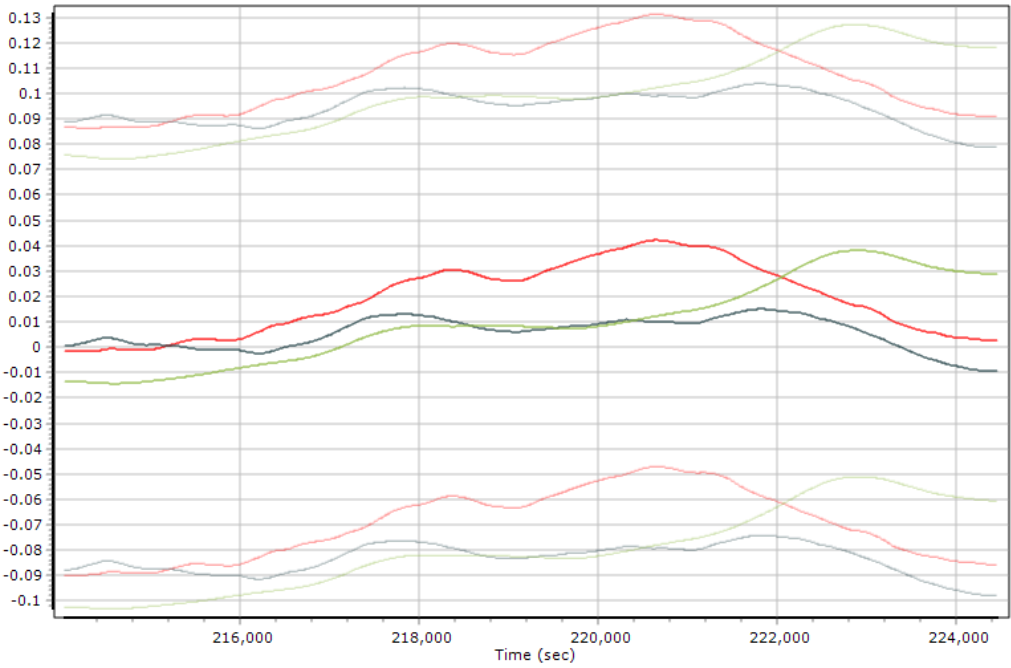
Sensor Errors



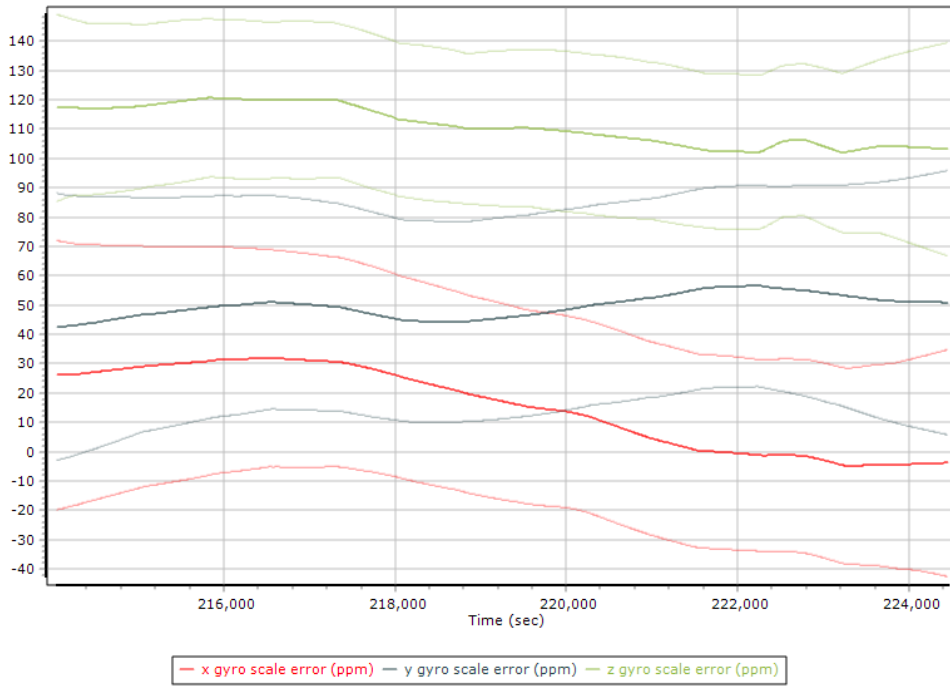
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



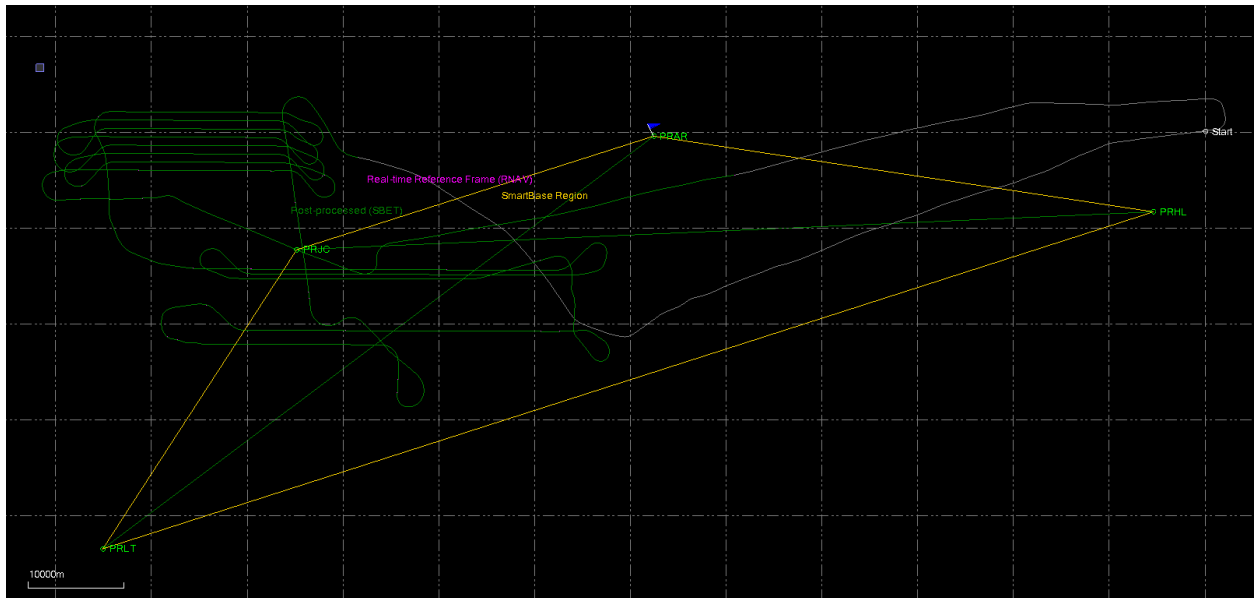
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

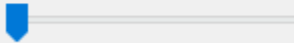


— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)



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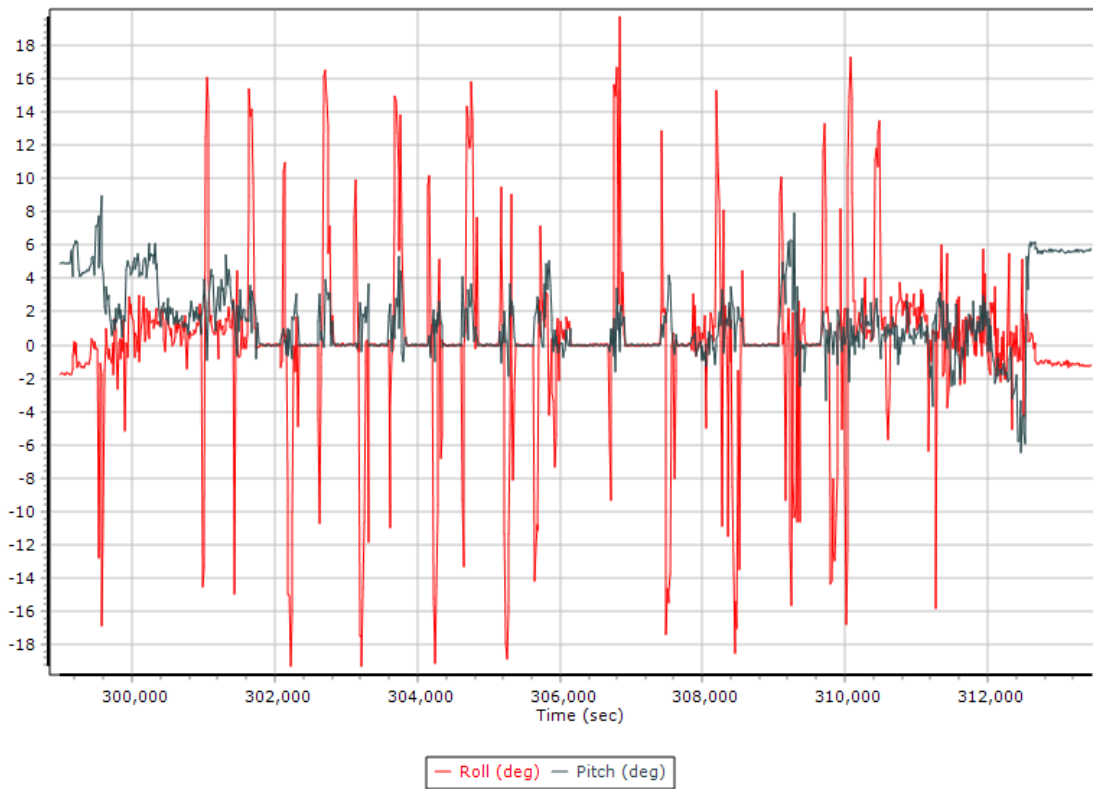
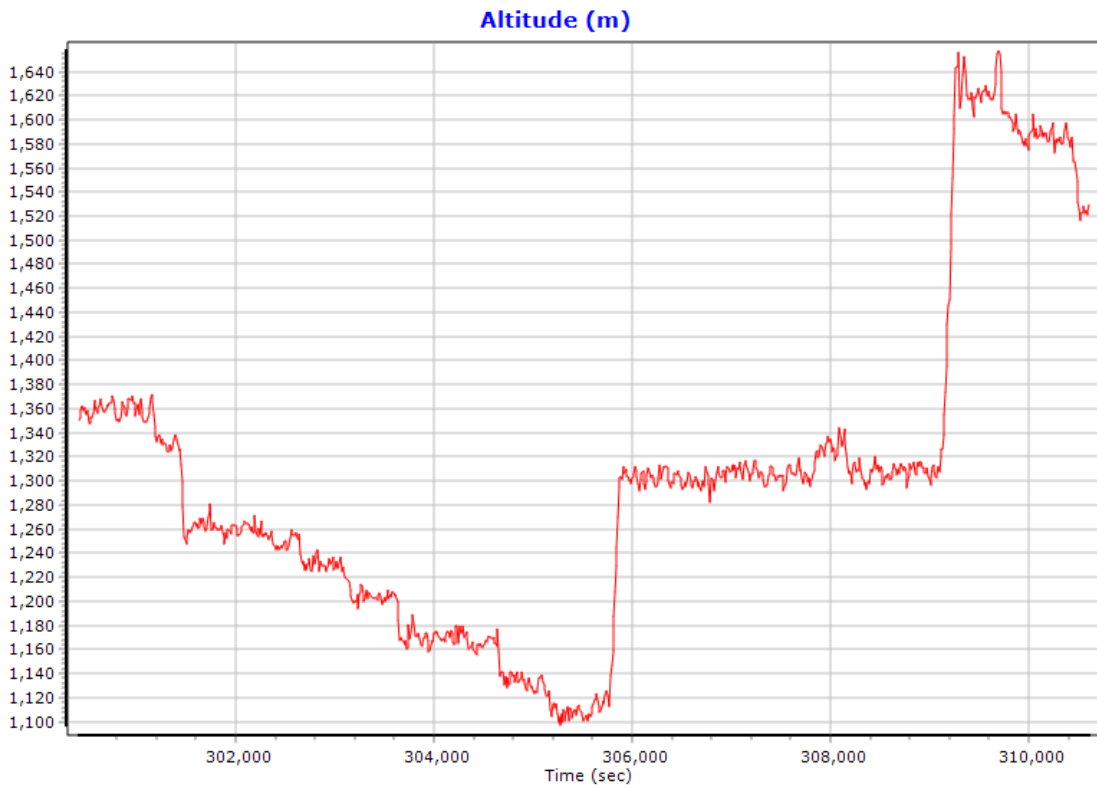


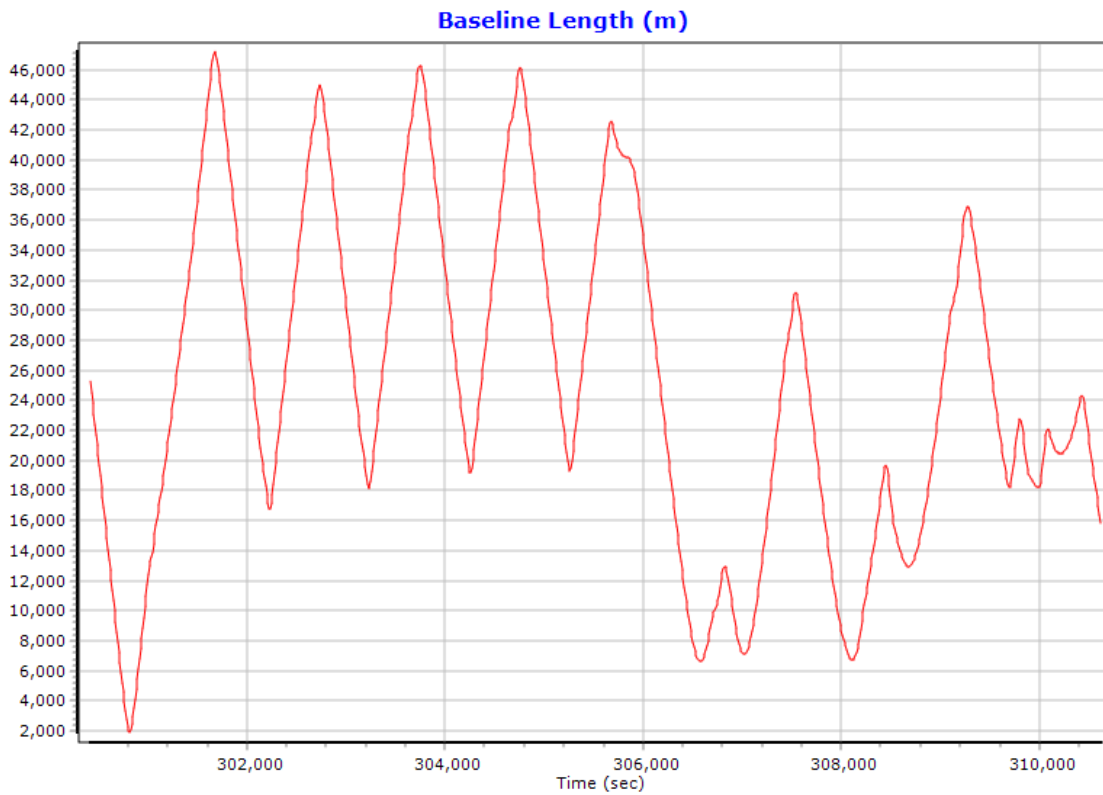
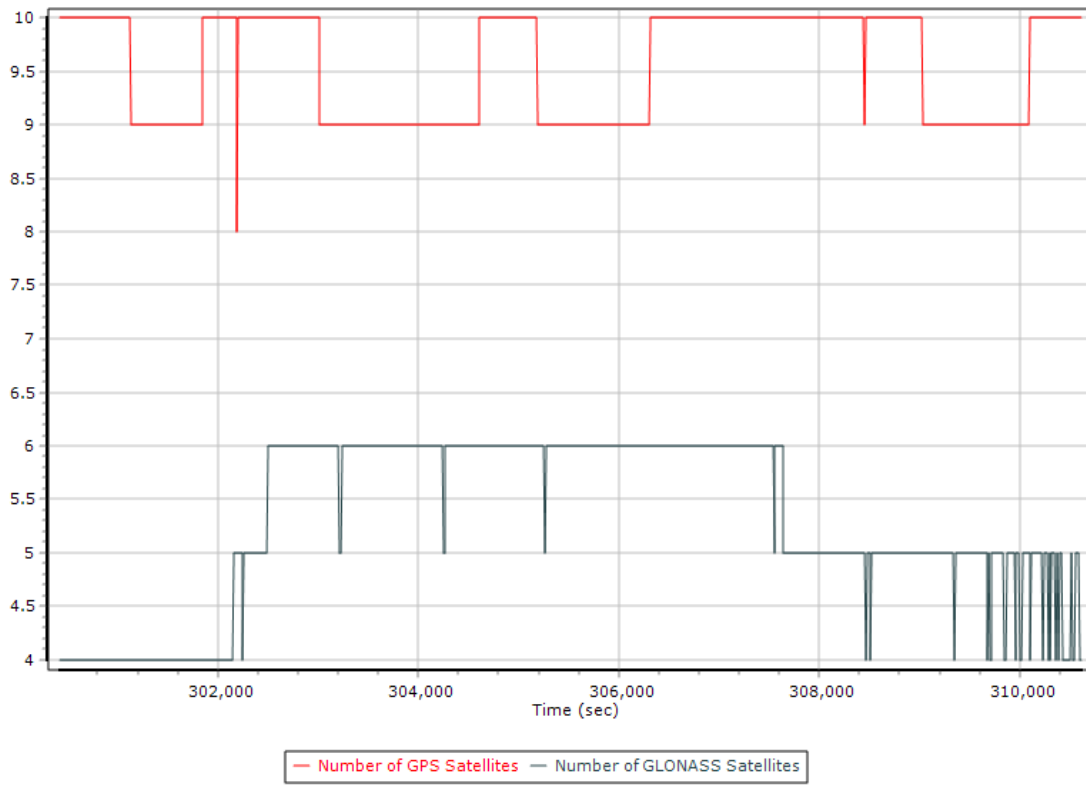
Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="-0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.010 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.352 m"/>	Z	<input type="text" value="0.000 deg"/>
Stabilized Mount to Primary GNSS Lever Arm		Aircraft to Stabilized Mount Mounting Angles	
X	<input type="text" value="-0.037 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="0.007 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.985 m"/>	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.

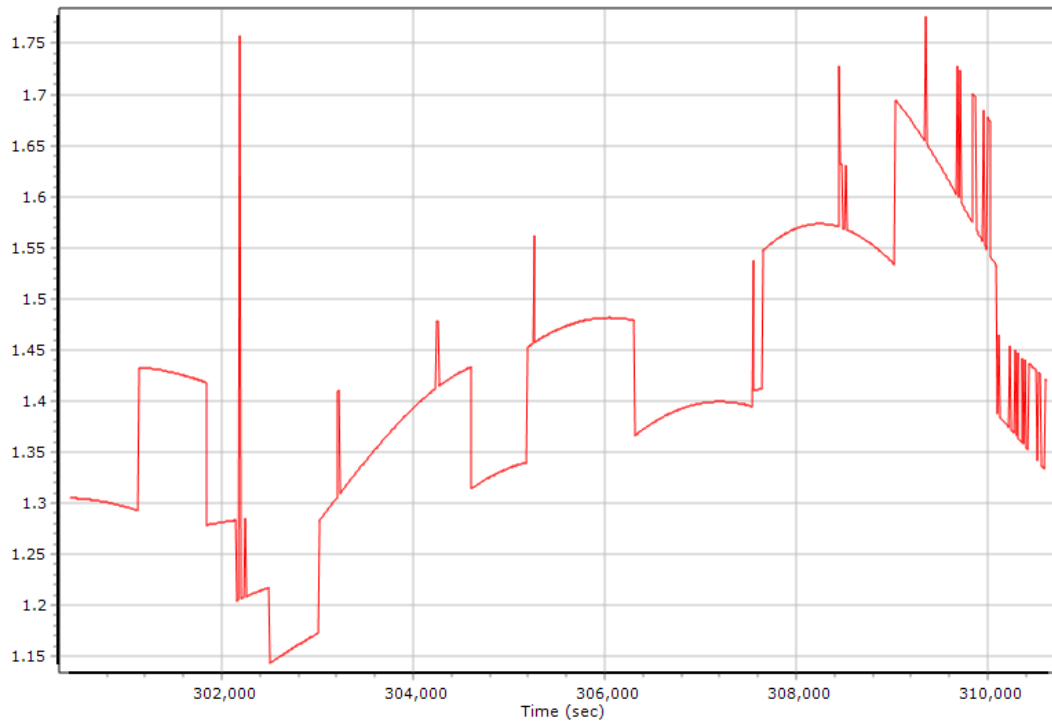
Timing

Start	<input type="text" value="300418.170"/>	Data	Incr. (sec)	^
End	<input type="text" value="310631.572"/>	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	v
UTC Offset	<input type="text" value="18.000"/>			

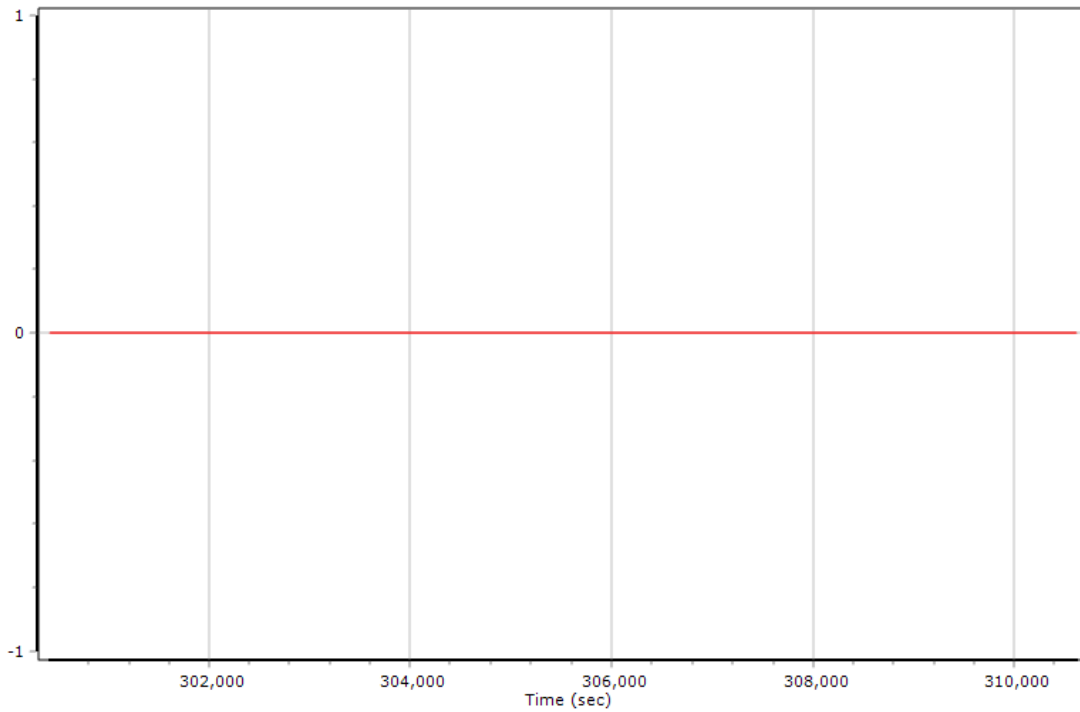




PDOP

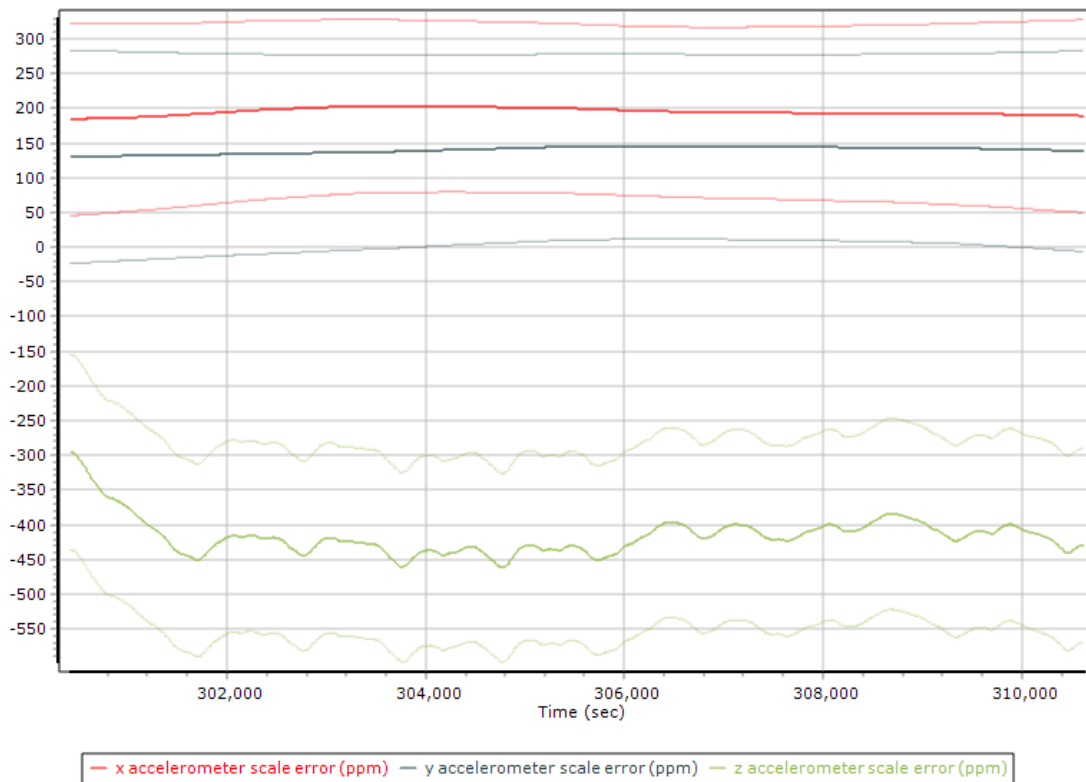
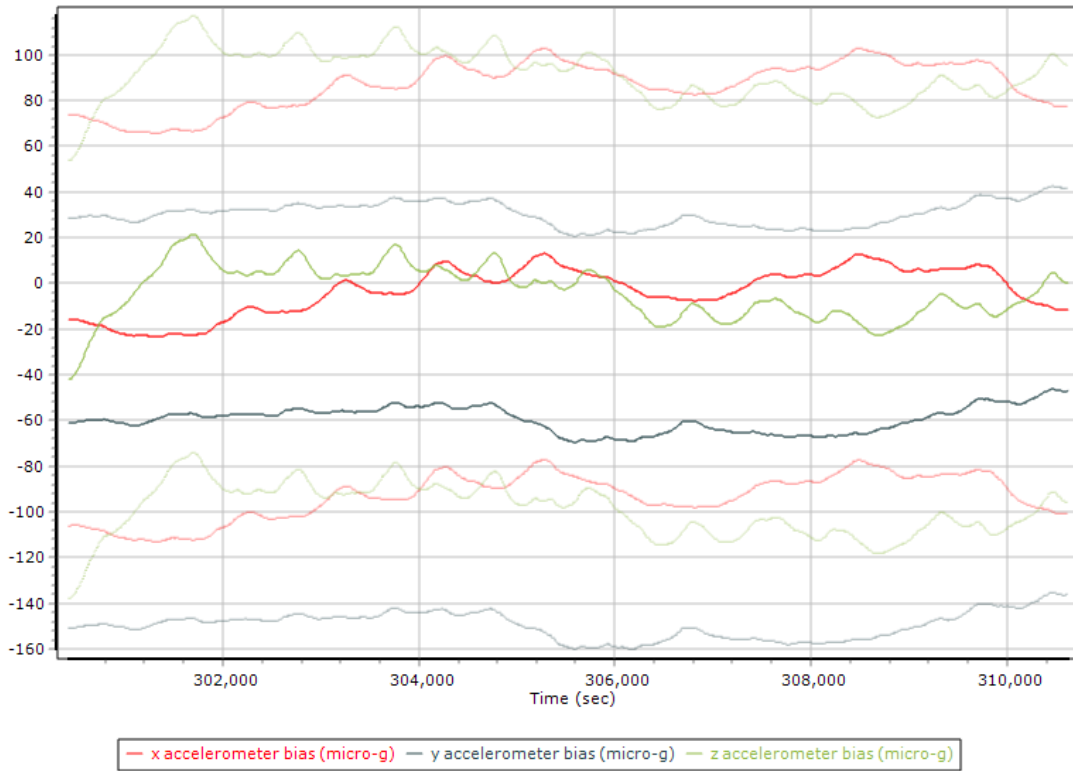


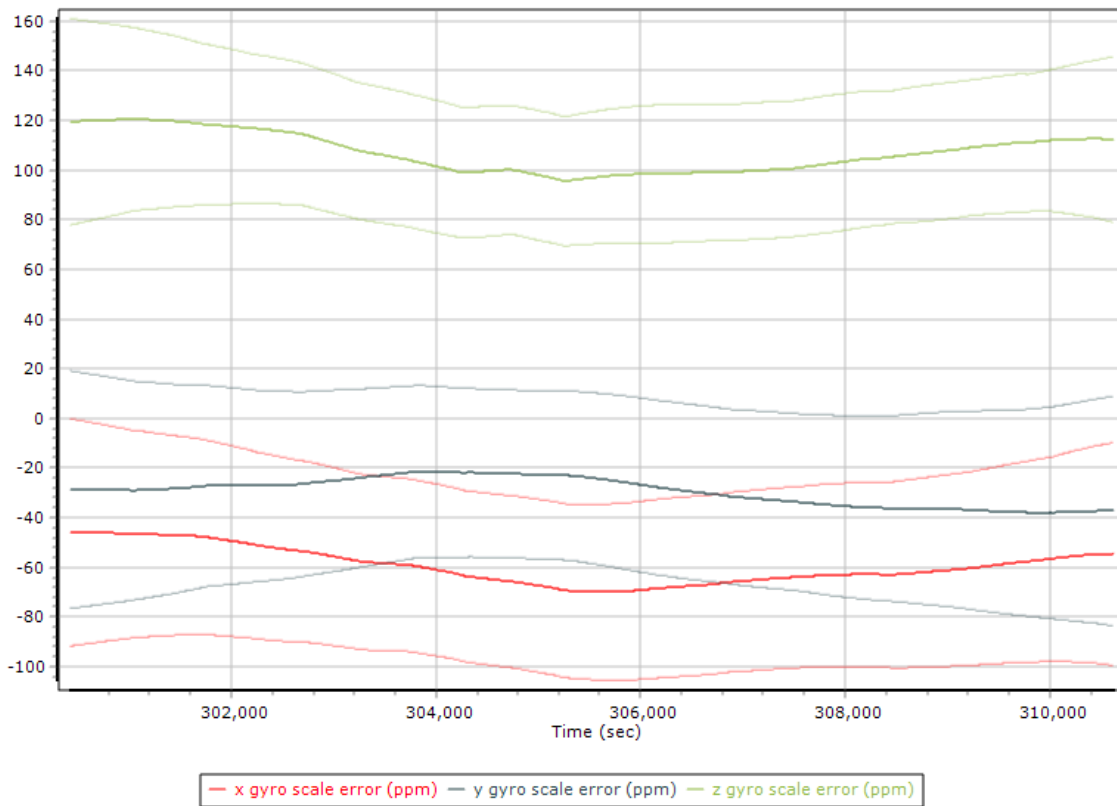
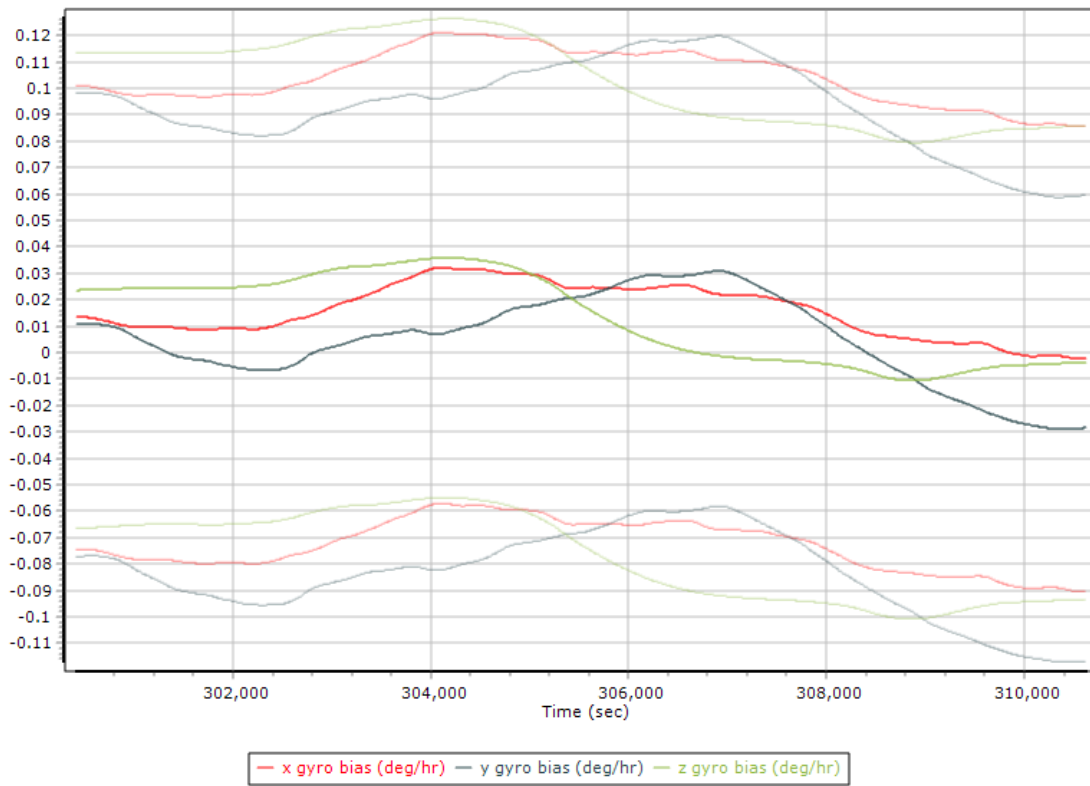
Processing mode



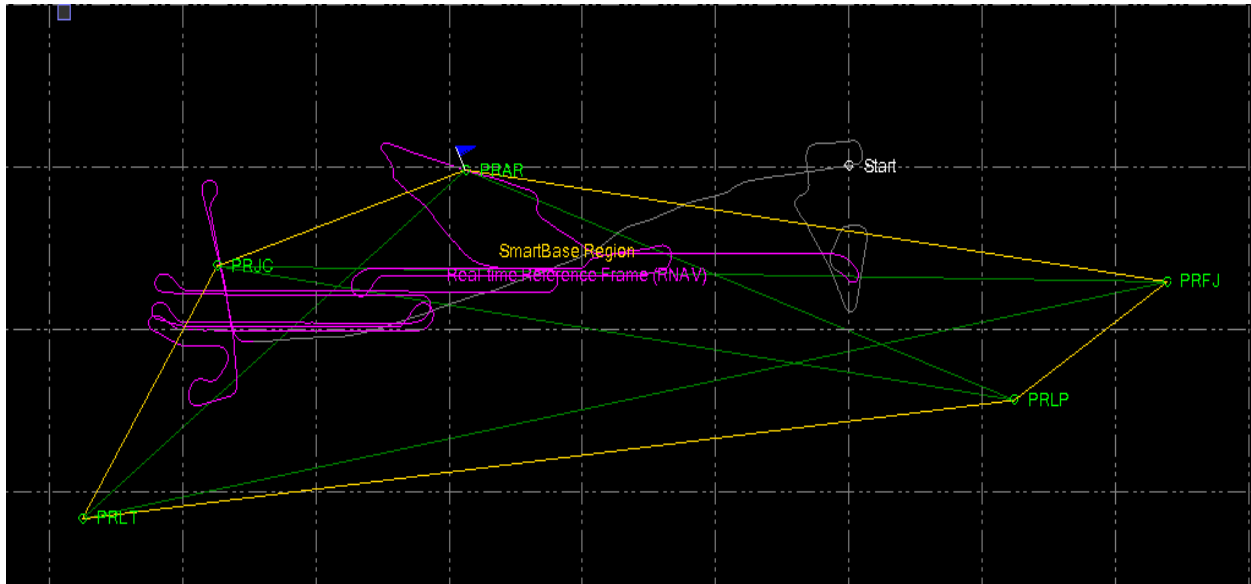
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





RBV18144A



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	-0.037 m	X	0.000 deg
Y	0.007 m	Y	0.000 deg
Z	-0.985 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

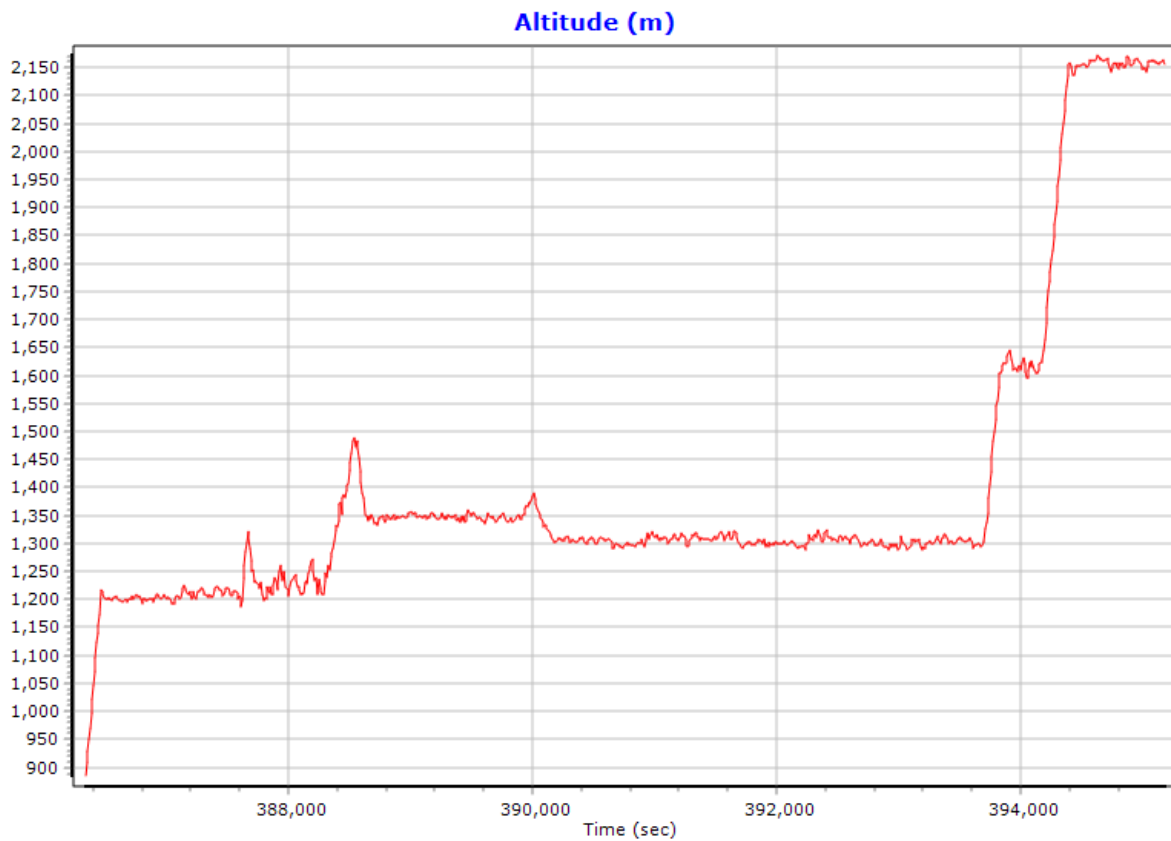
Timing

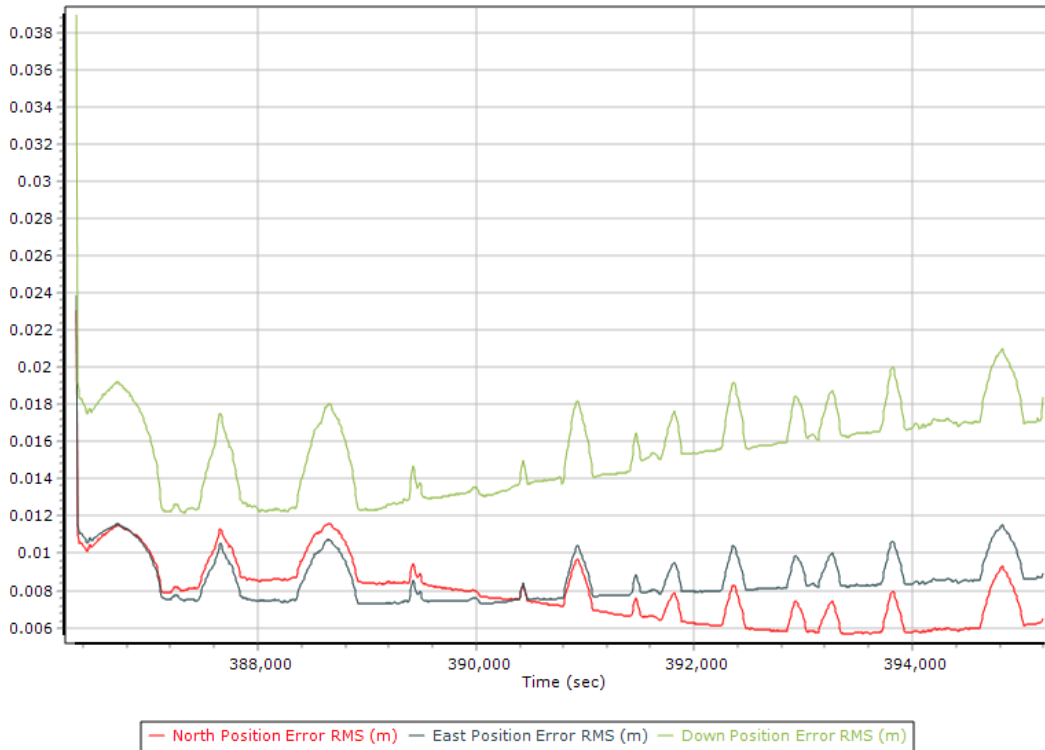
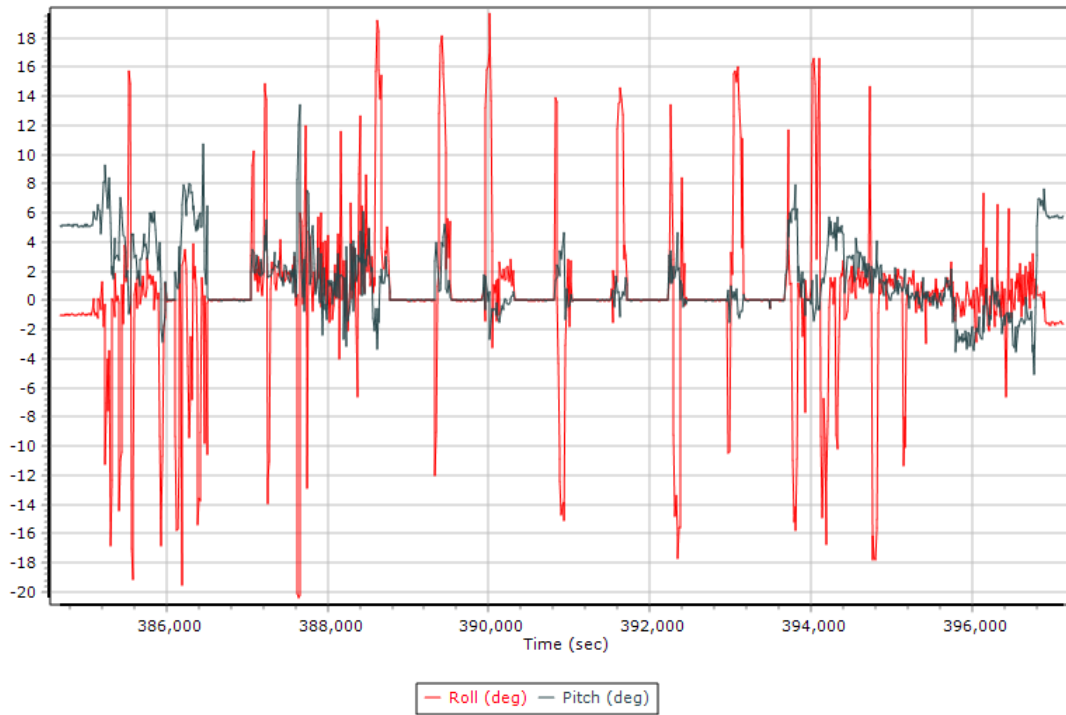
Start: 386330.203
End: 395205.285
UTC Offset: 18.000

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

Entire time interval:
Seconds of start week:

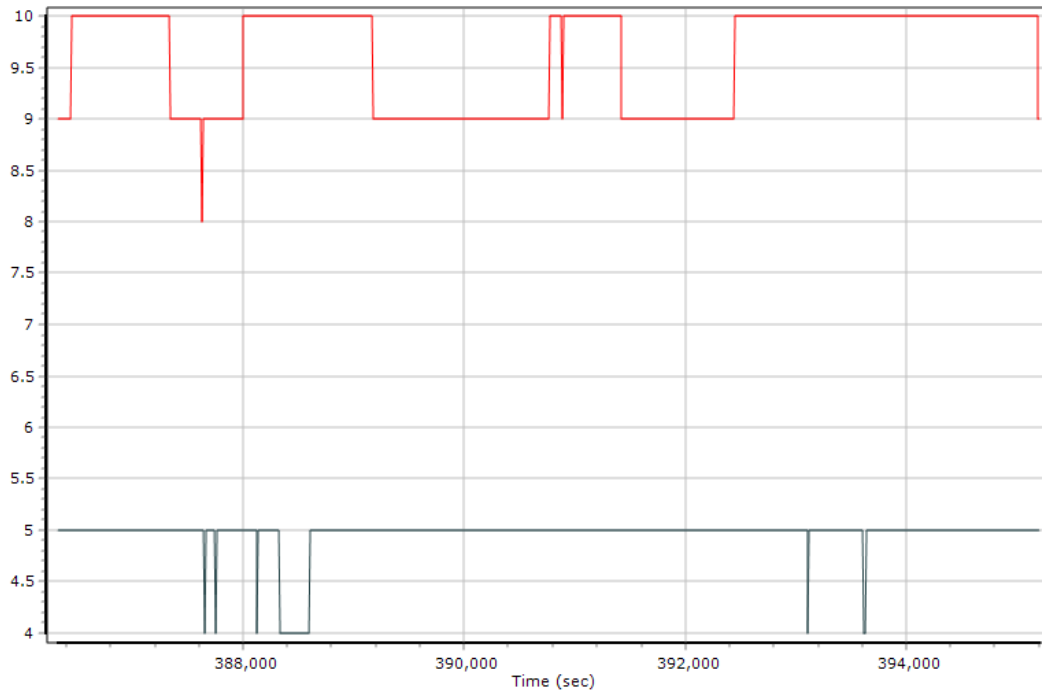
OK Cancel



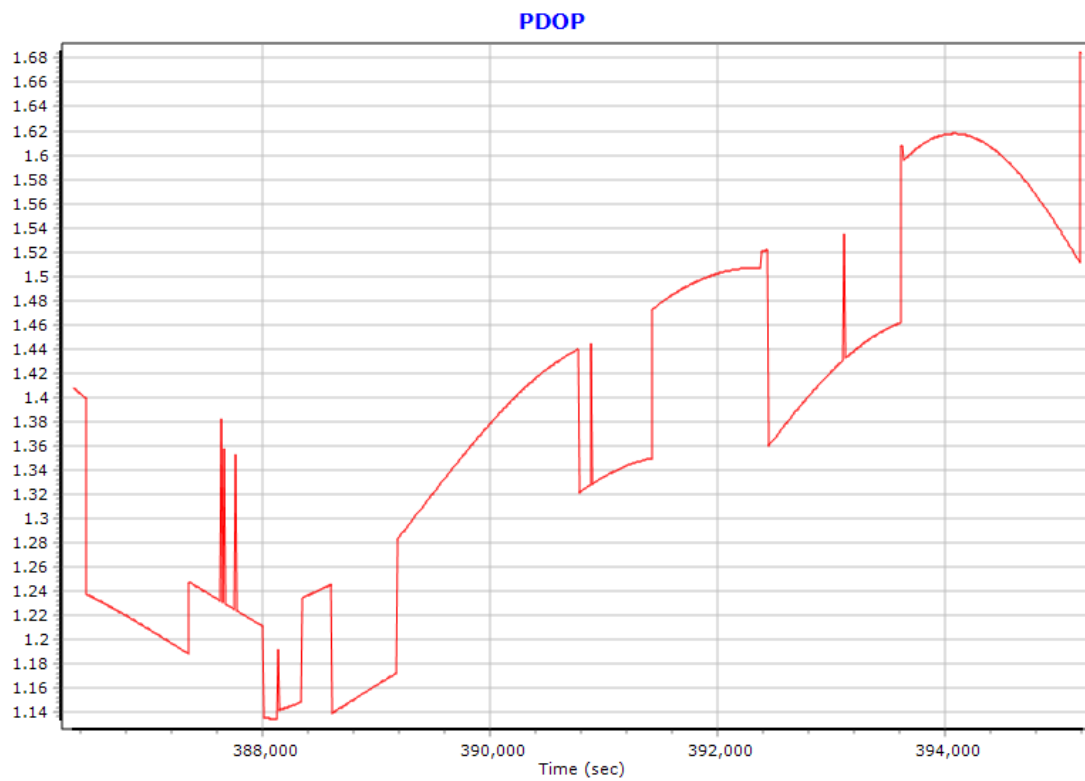
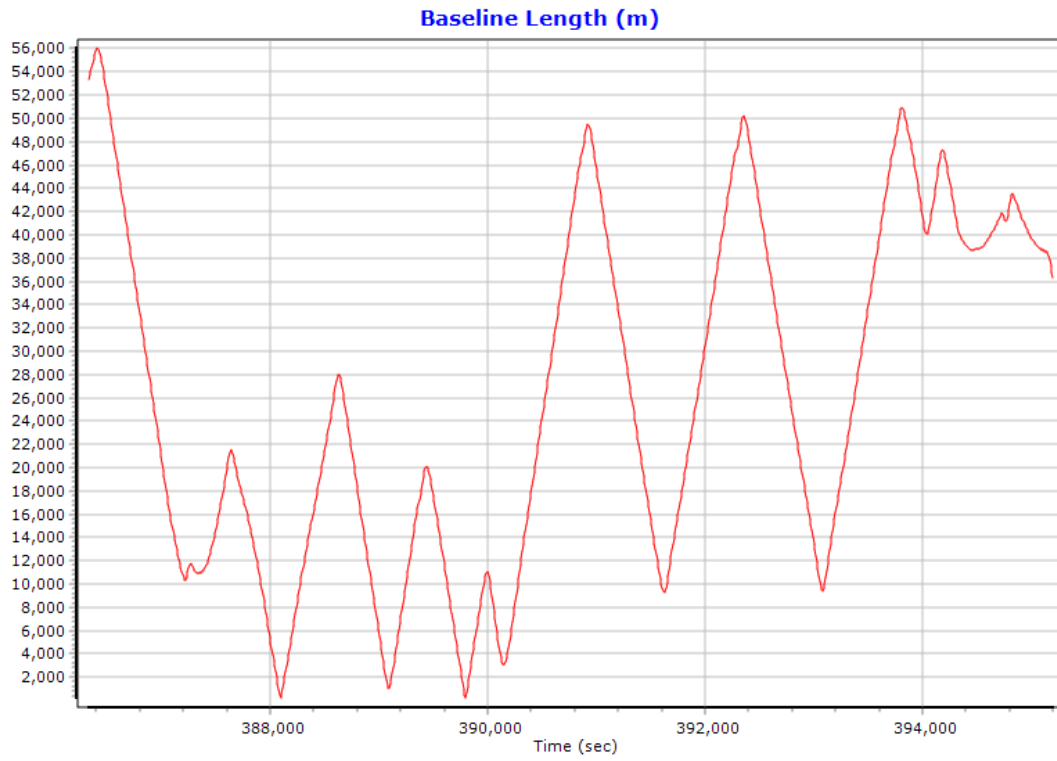




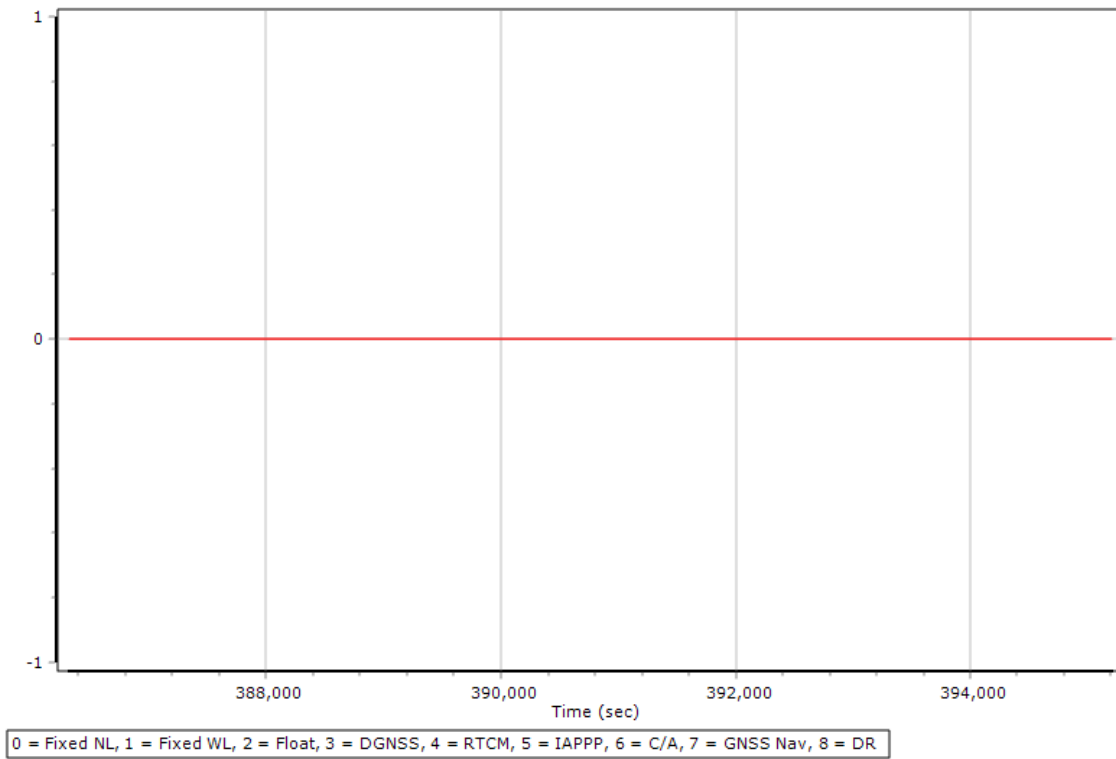
— North (m) — East (m) — Down (m) — DR mode



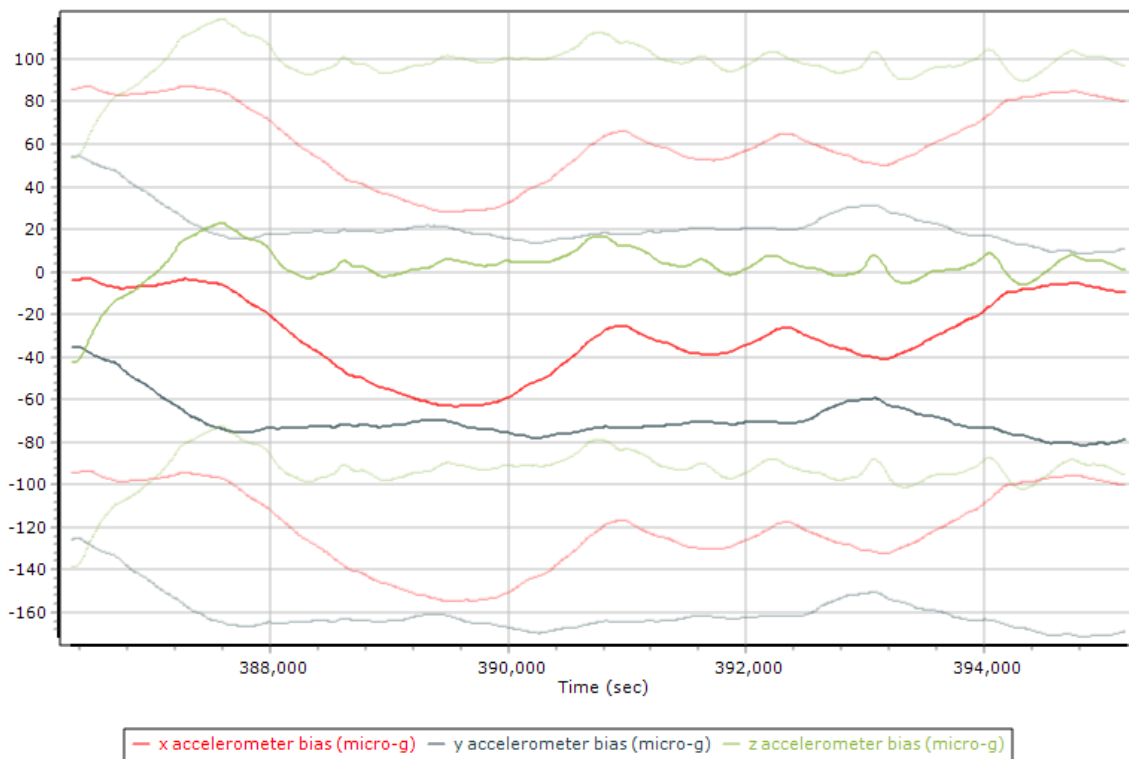
— Number of GPS Satellites — Number of GLONASS Satellites

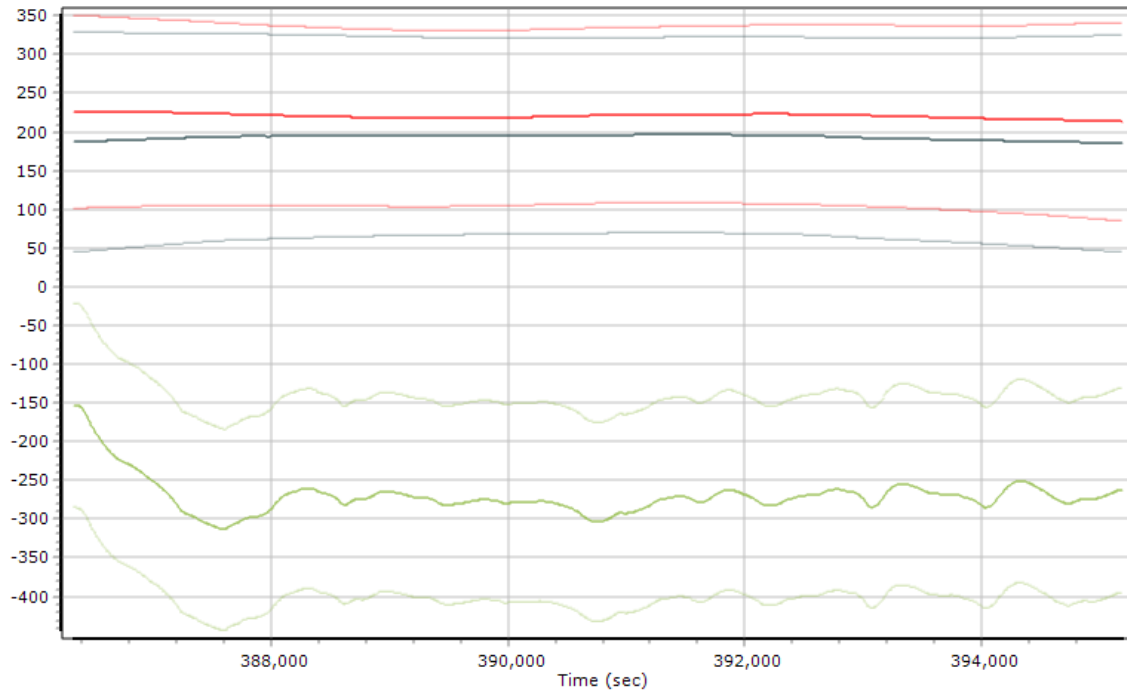


Processing mode

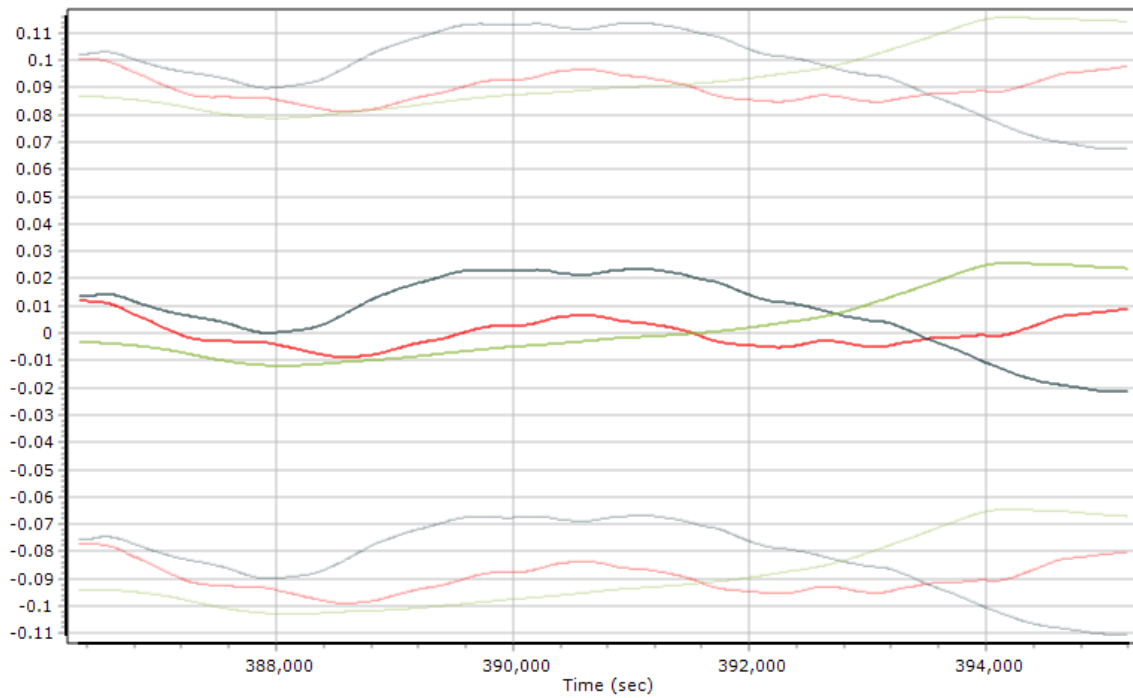


Sensor Errors

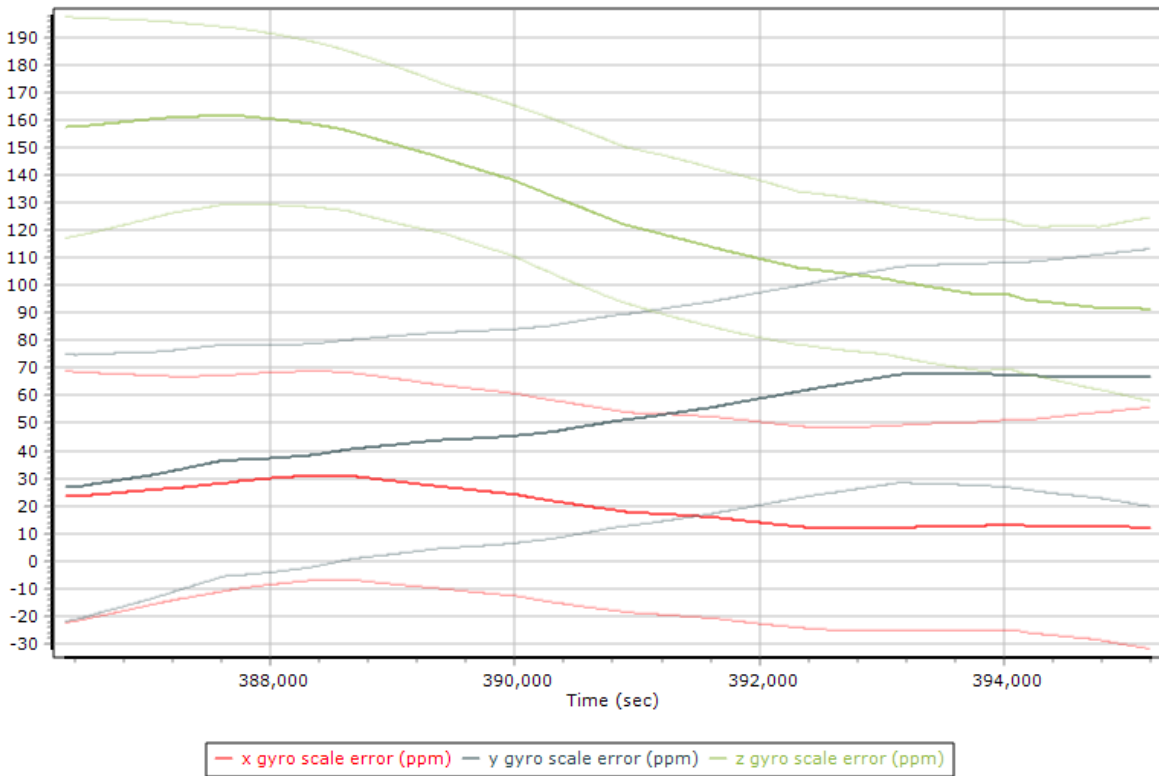




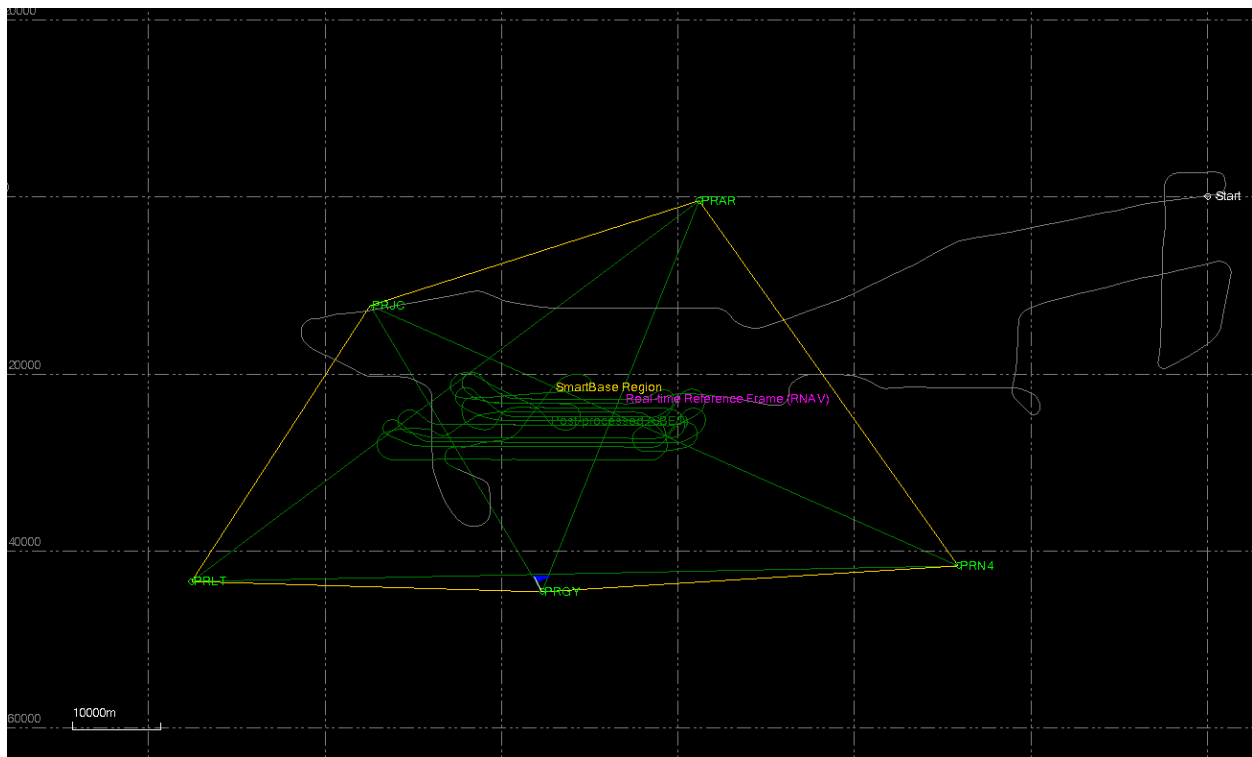
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



RBV18145A



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: -0.034 m
Y: -0.010 m
Z: -0.352 m

Stabilized Mount to IMU Mounting Angles
X: 0.000 deg
Y: 0.000 deg
Z: 0.000 deg

Stabilized Mount to Primary GNSS Lever Arm
X: -0.037 m
Y: 0.007 m
Z: -0.985 m

Aircraft to Stabilized Mount Mounting Angles
X: 0.000 deg
Y: 0.000 deg
Z: 0.000 deg

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

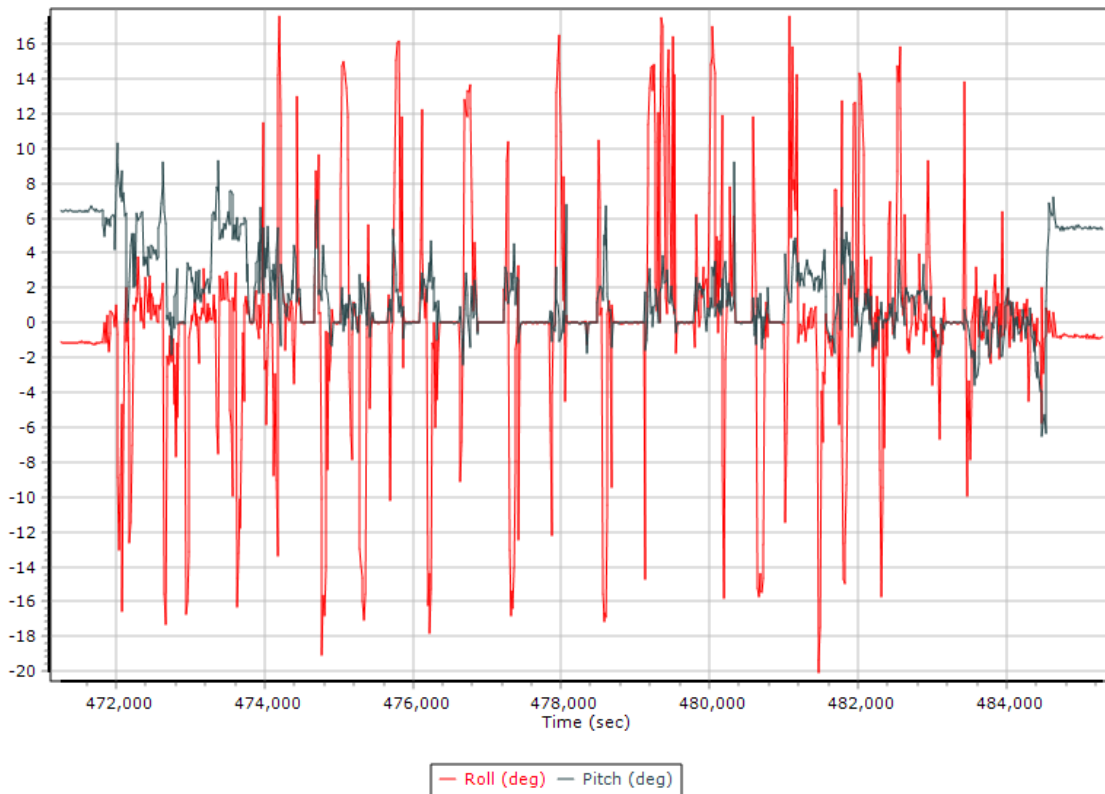
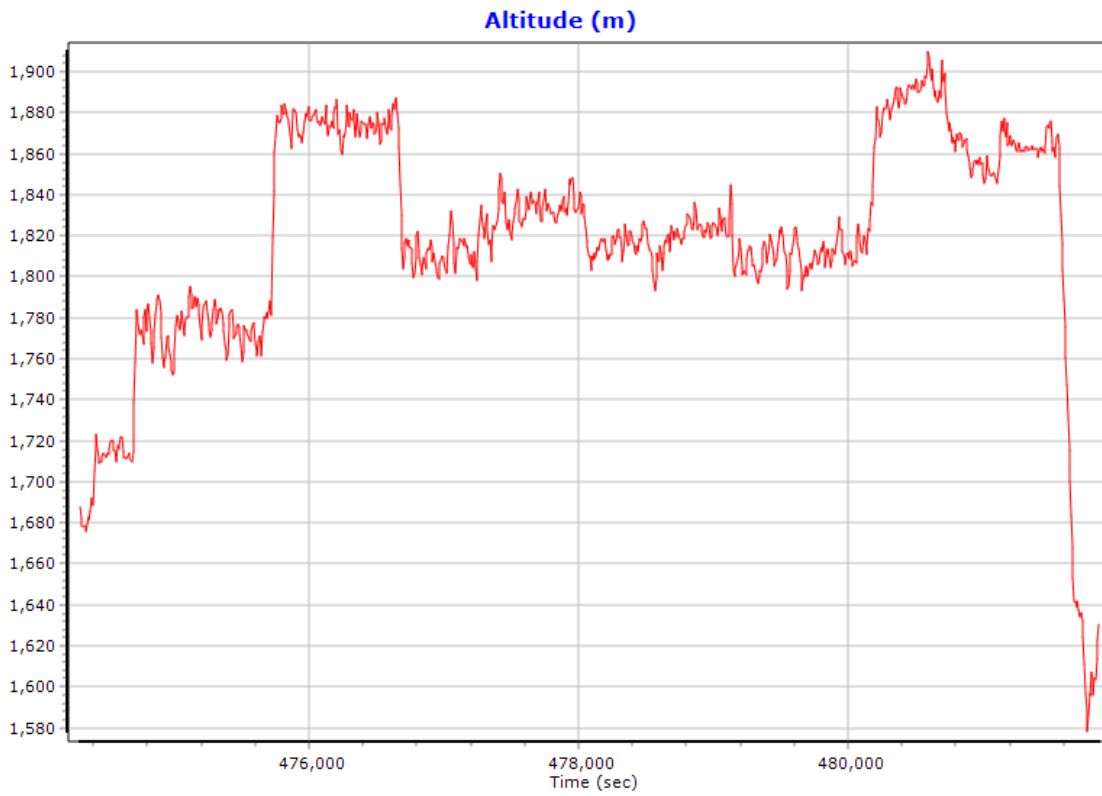
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

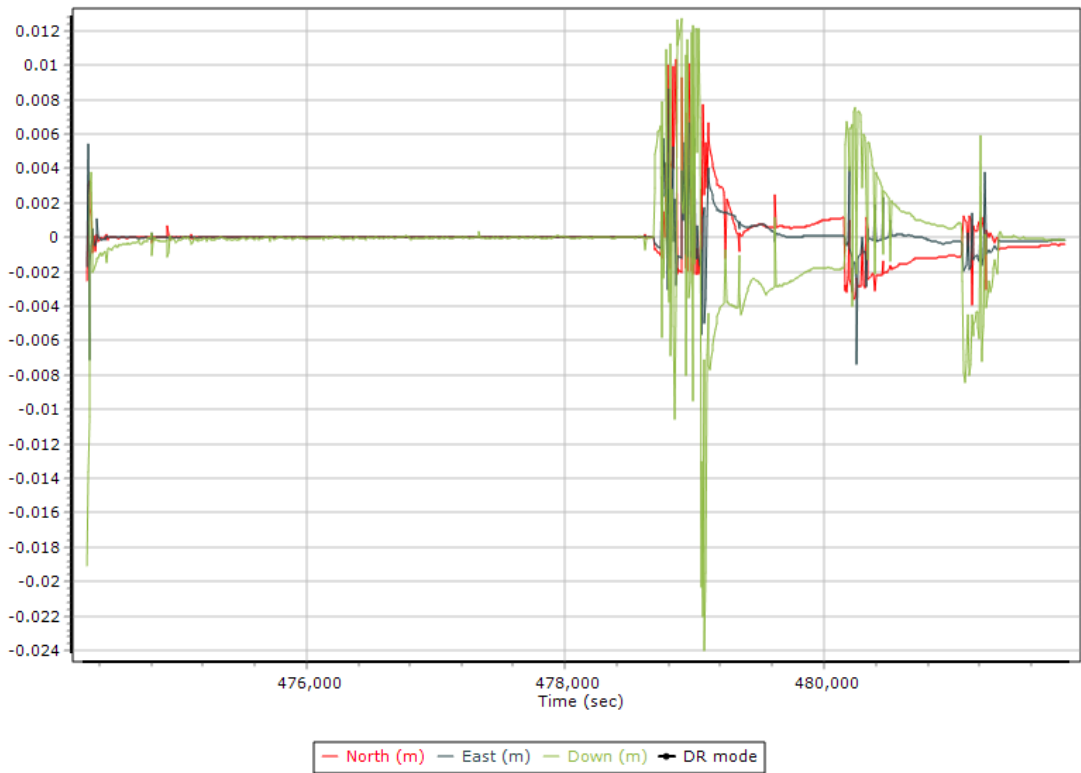
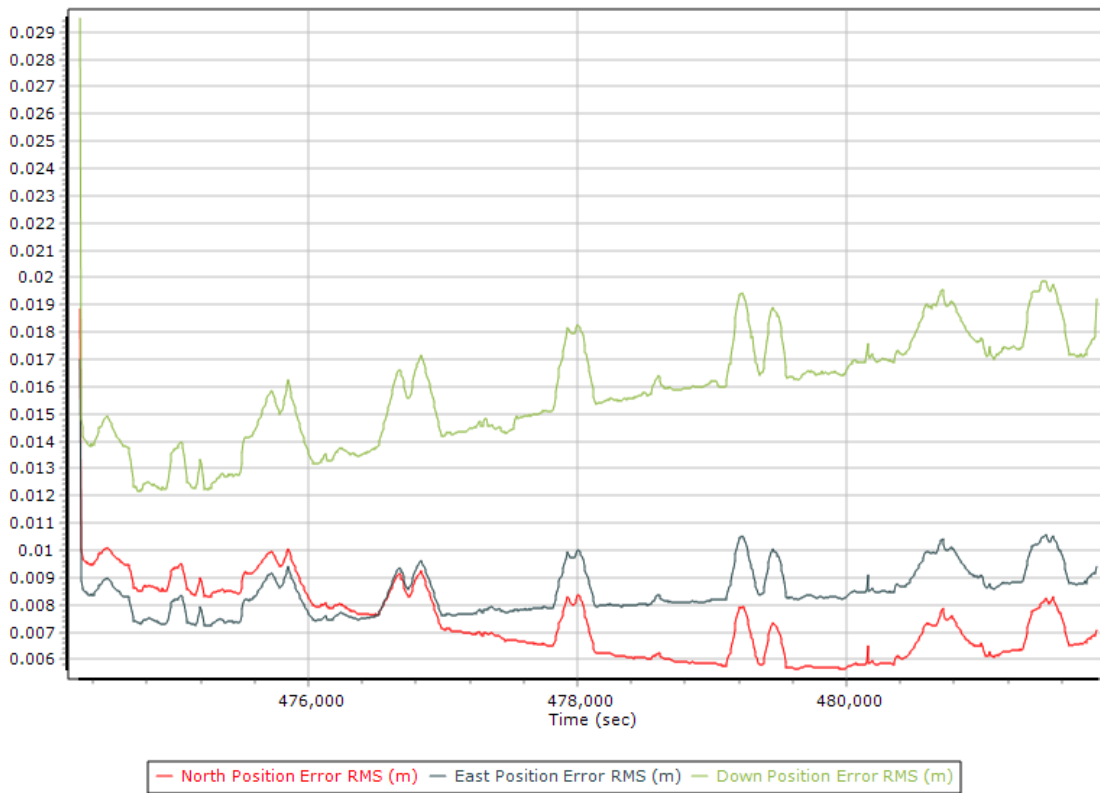
OK Cancel

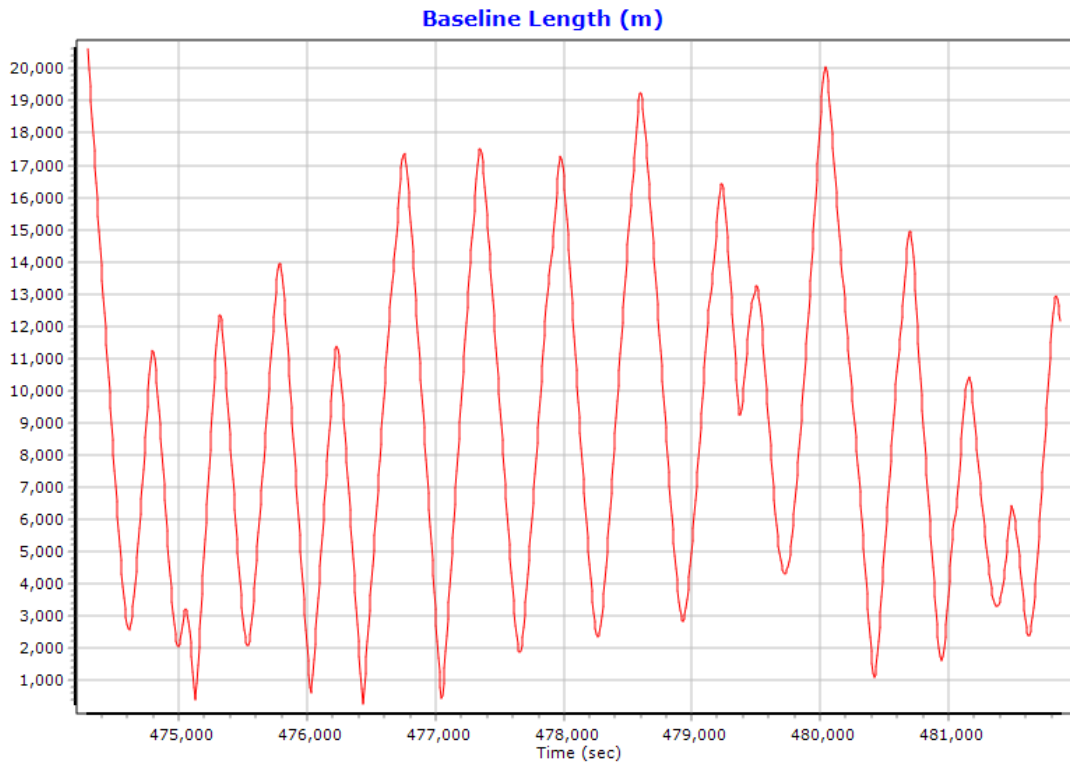
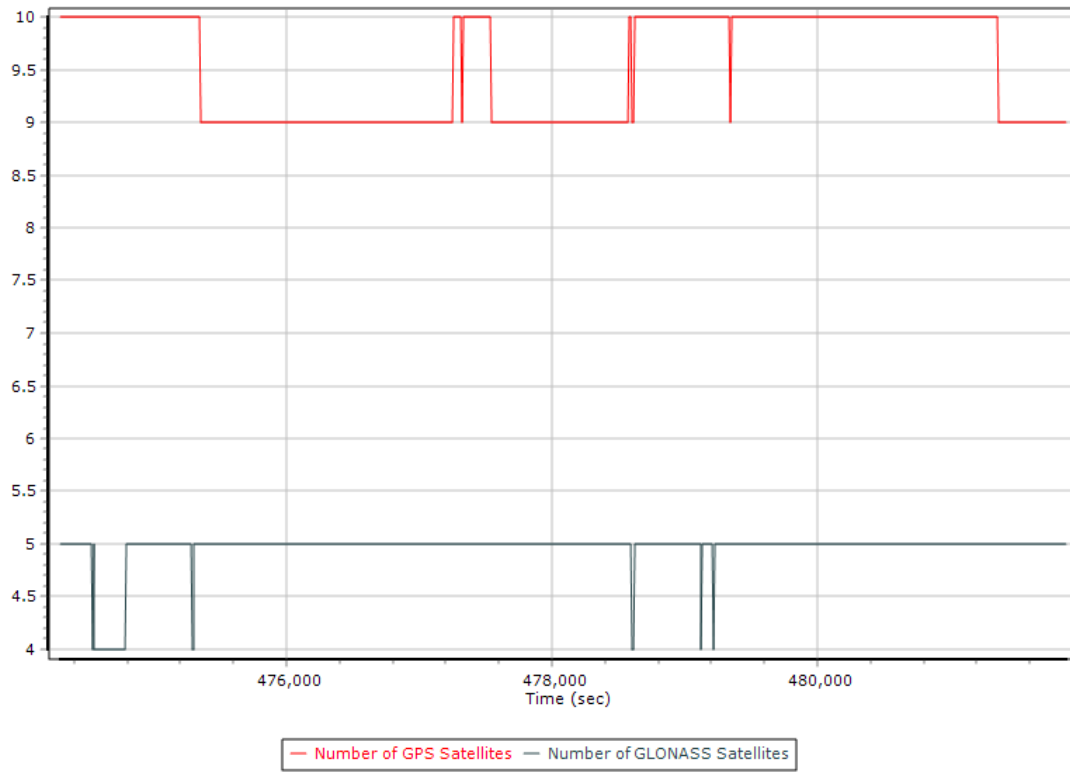
Timing

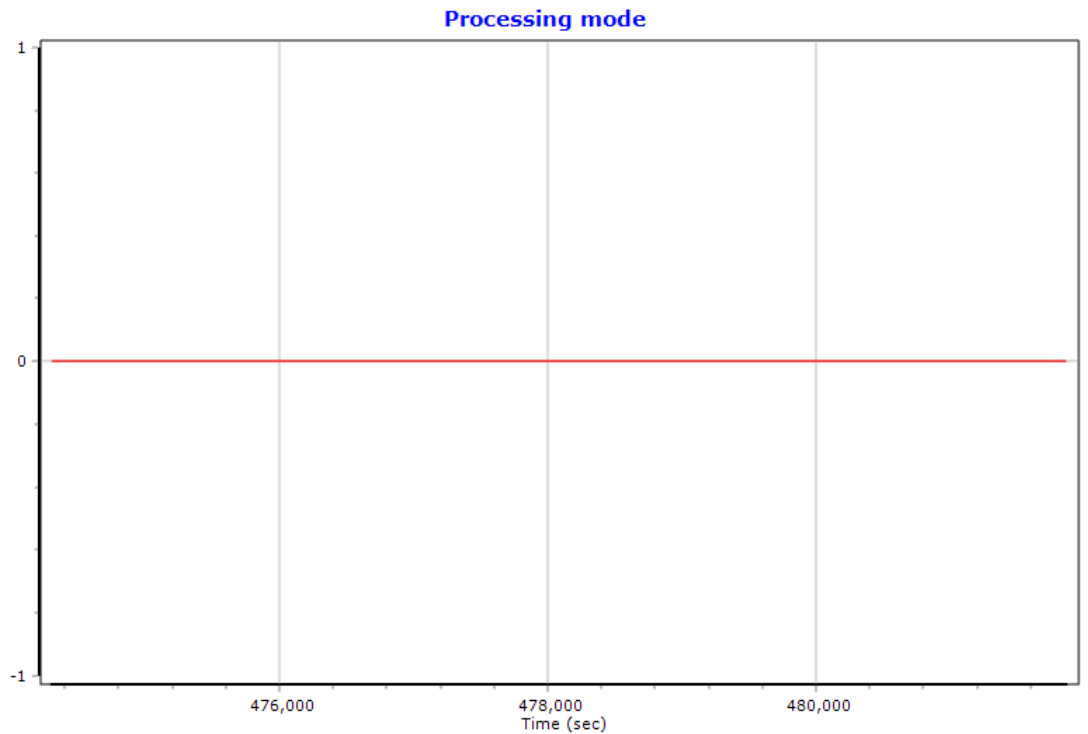
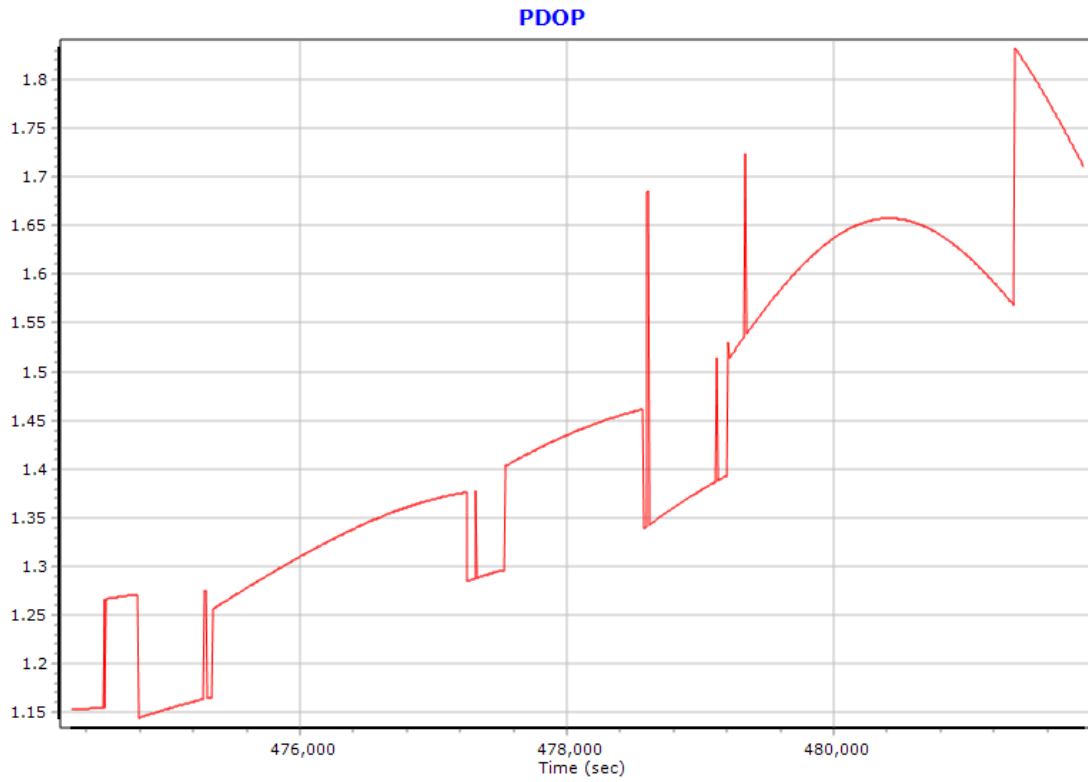
Start: 474294.985
End: 481872.764
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

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



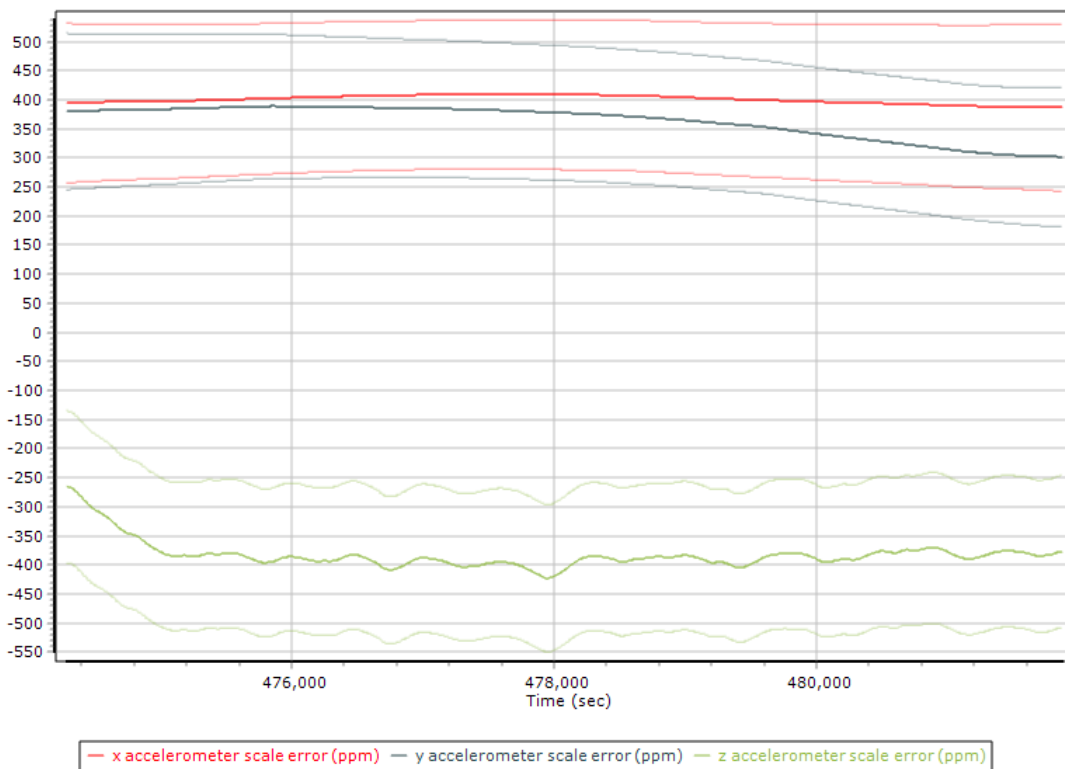
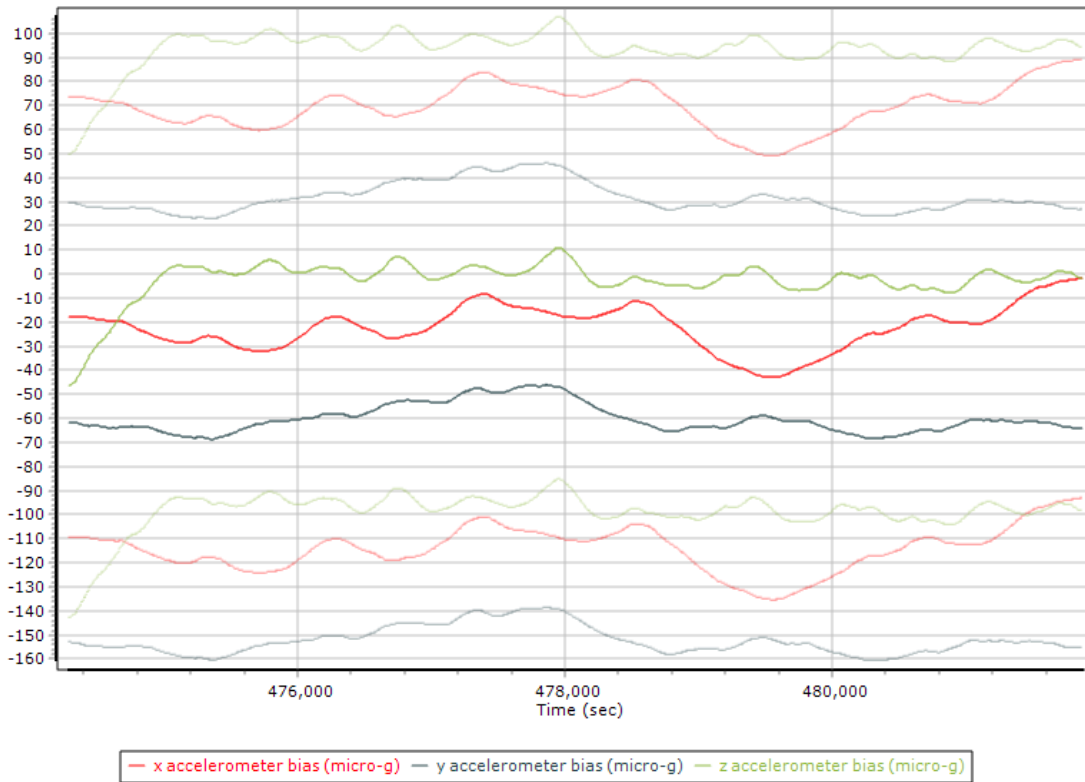


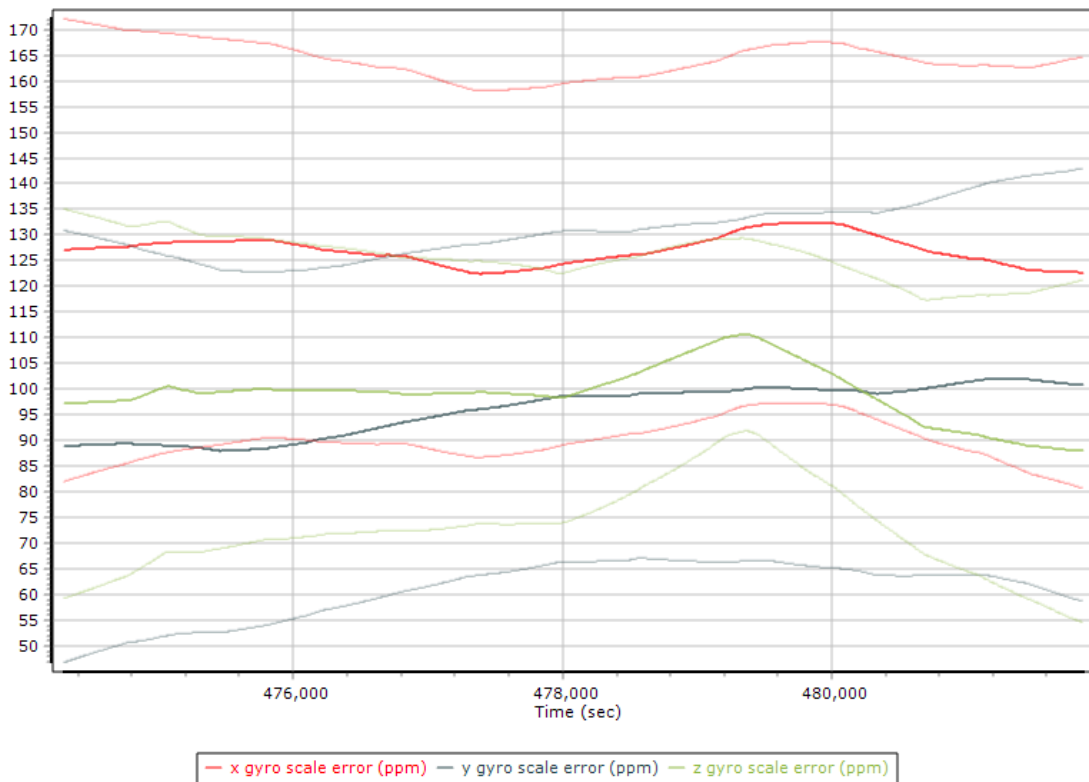
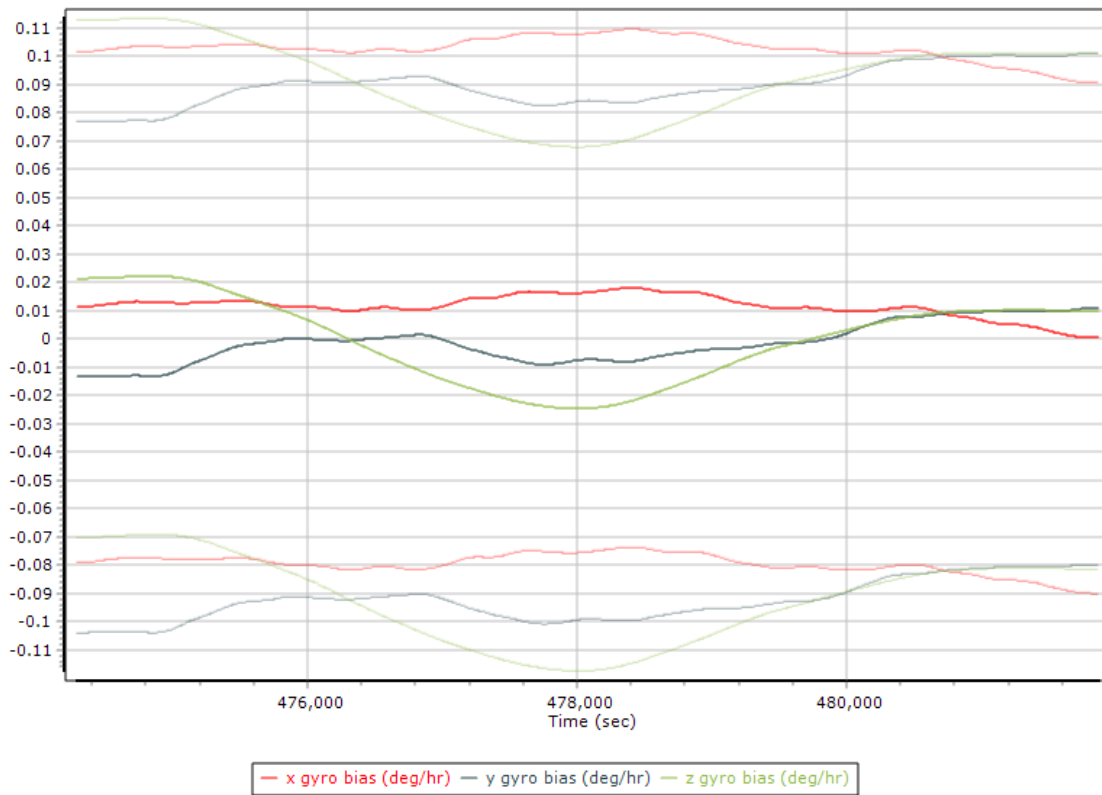




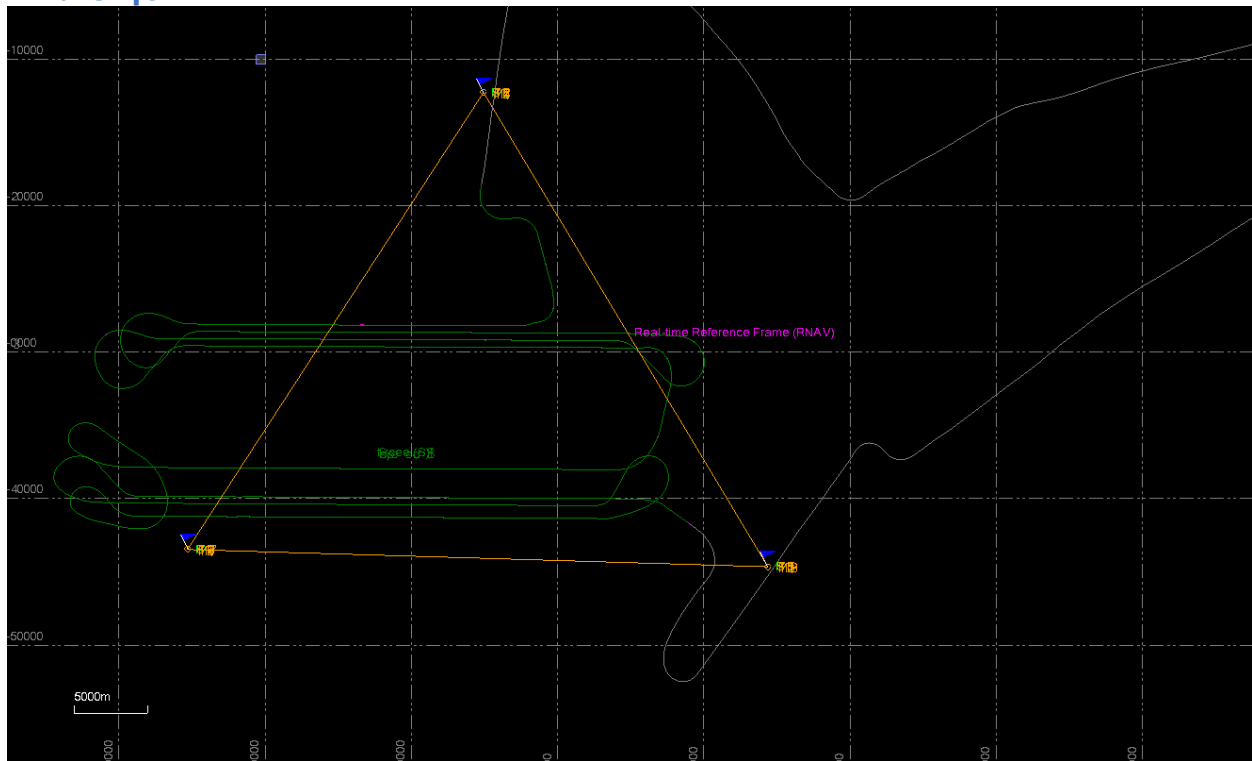
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





RBV18146A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angle
- 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: -0.037 m	X: 0.000 deg
Y: 0.007 m	Y: 0.000 deg
Z: -0.985 m	Z: 0.000 deg

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

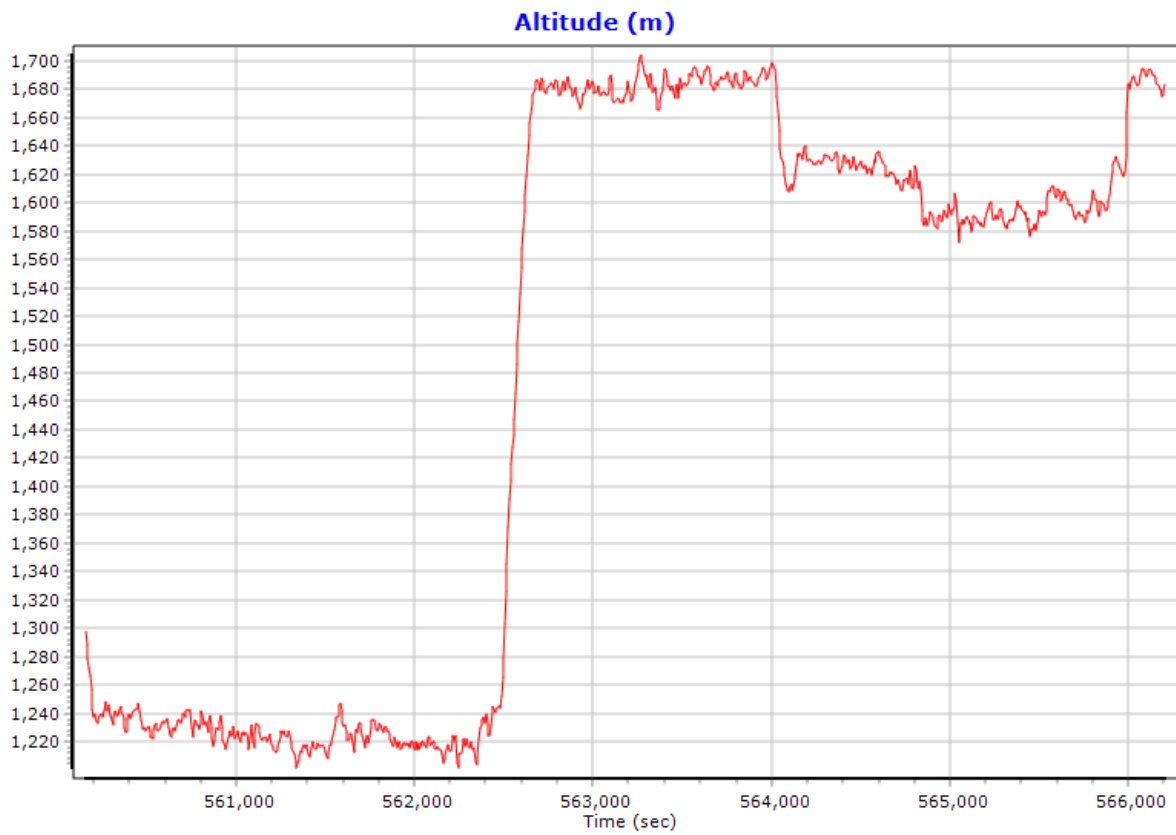
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

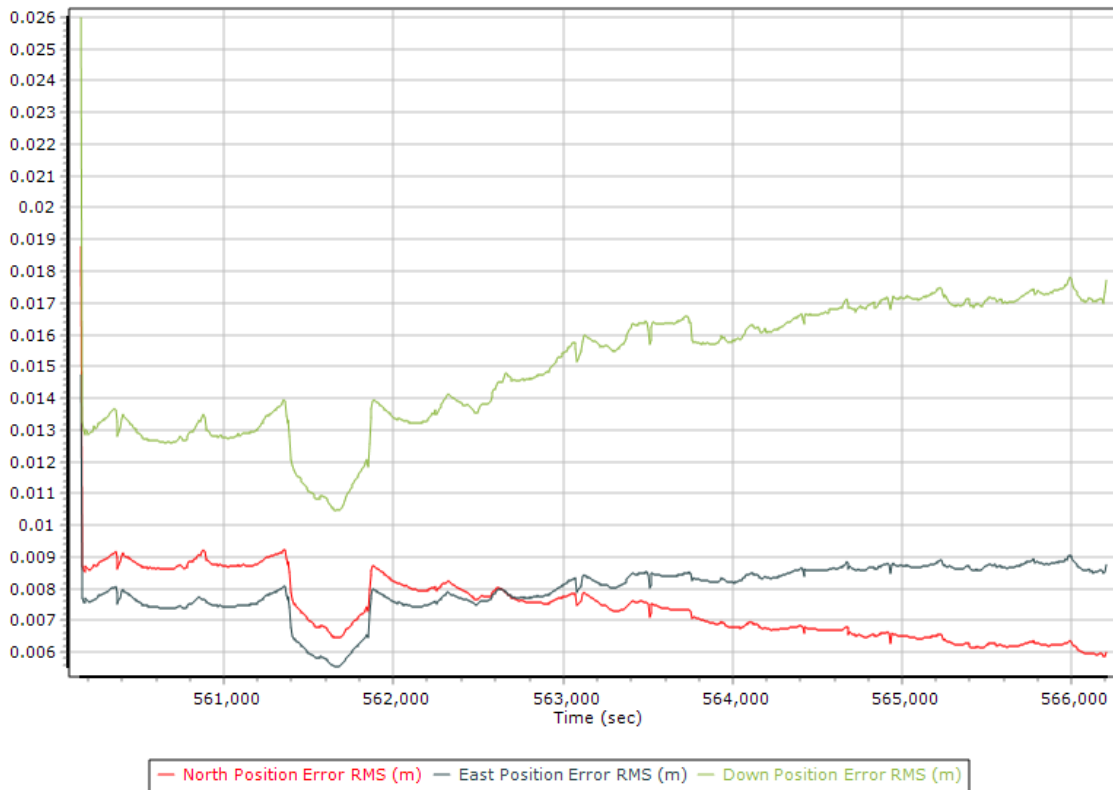
OK Cancel

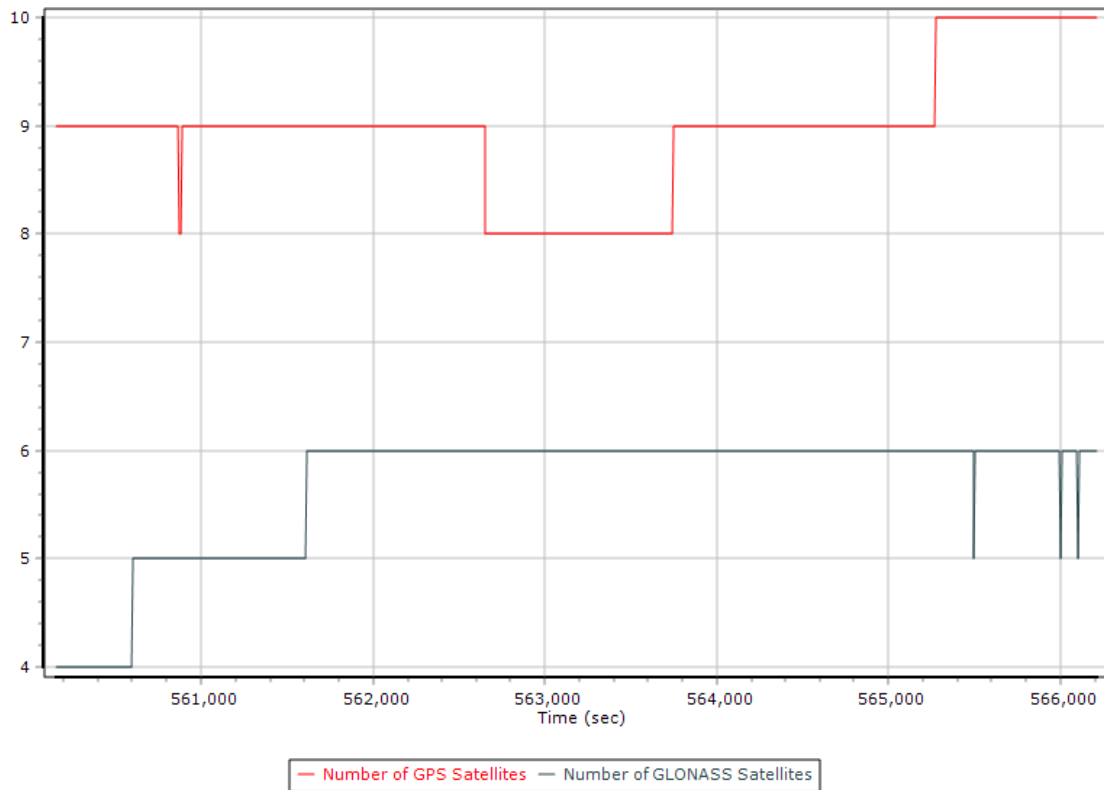
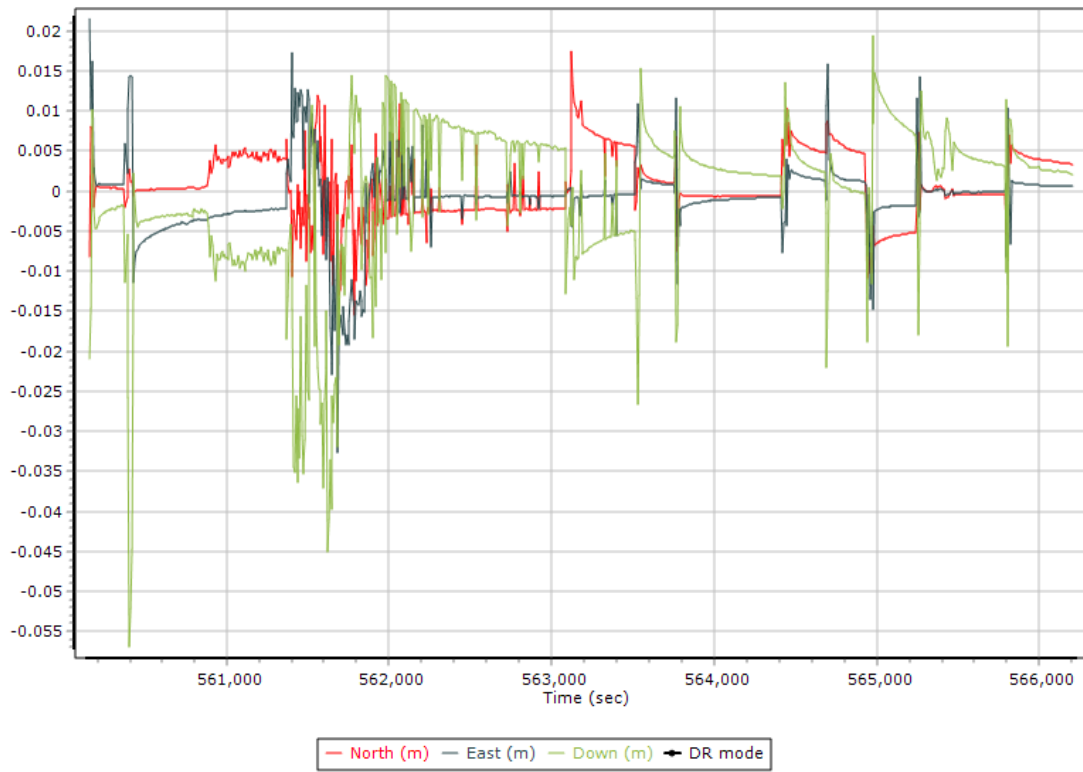
Timing

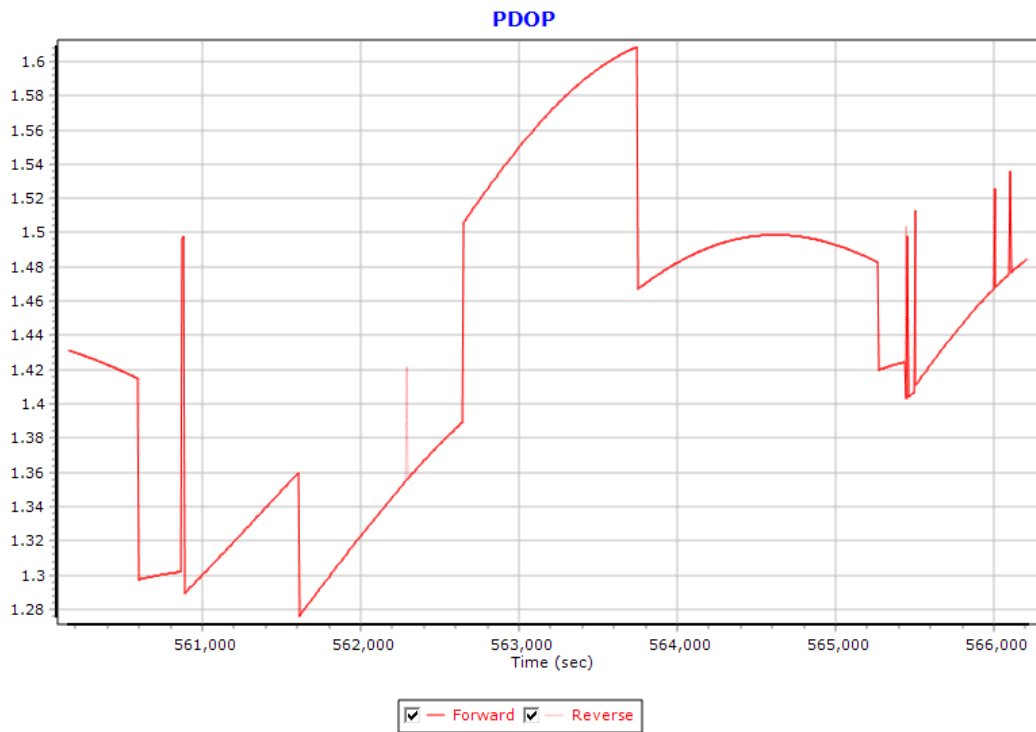
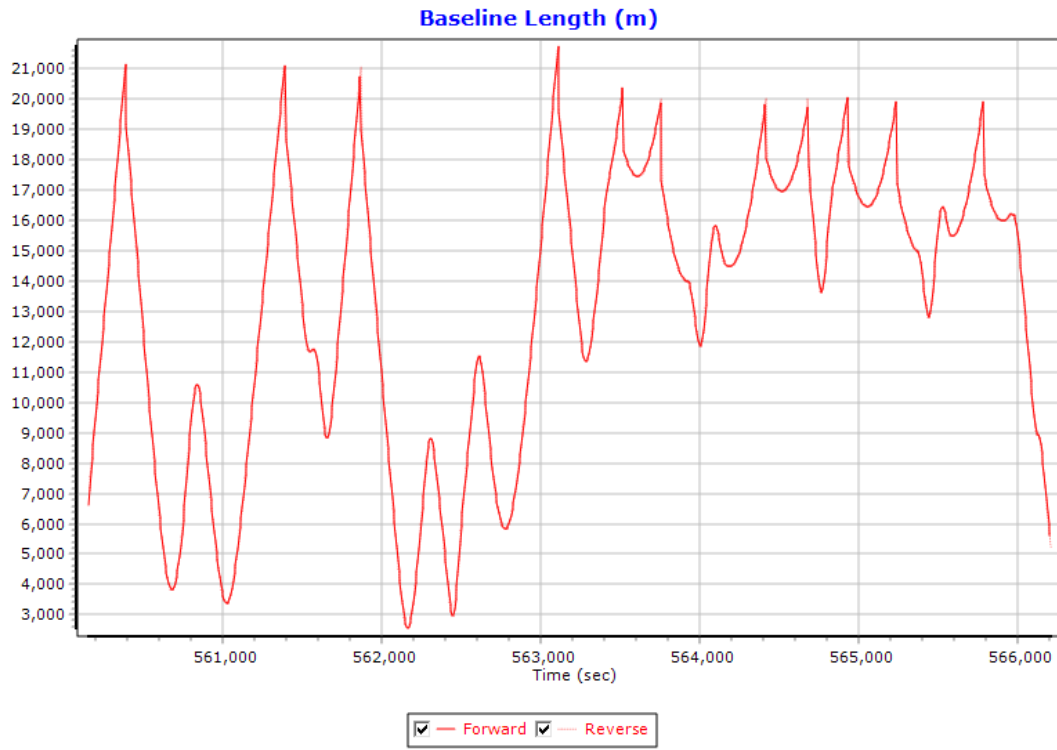
Start	560153.908	Data	Incr. (sec)
End	566213.330	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset 18.000

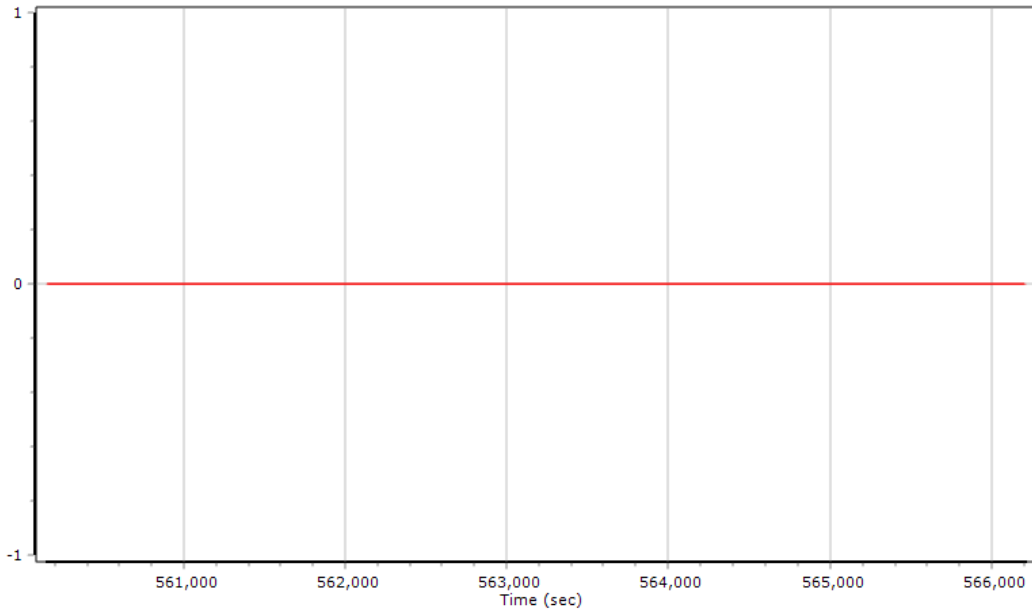








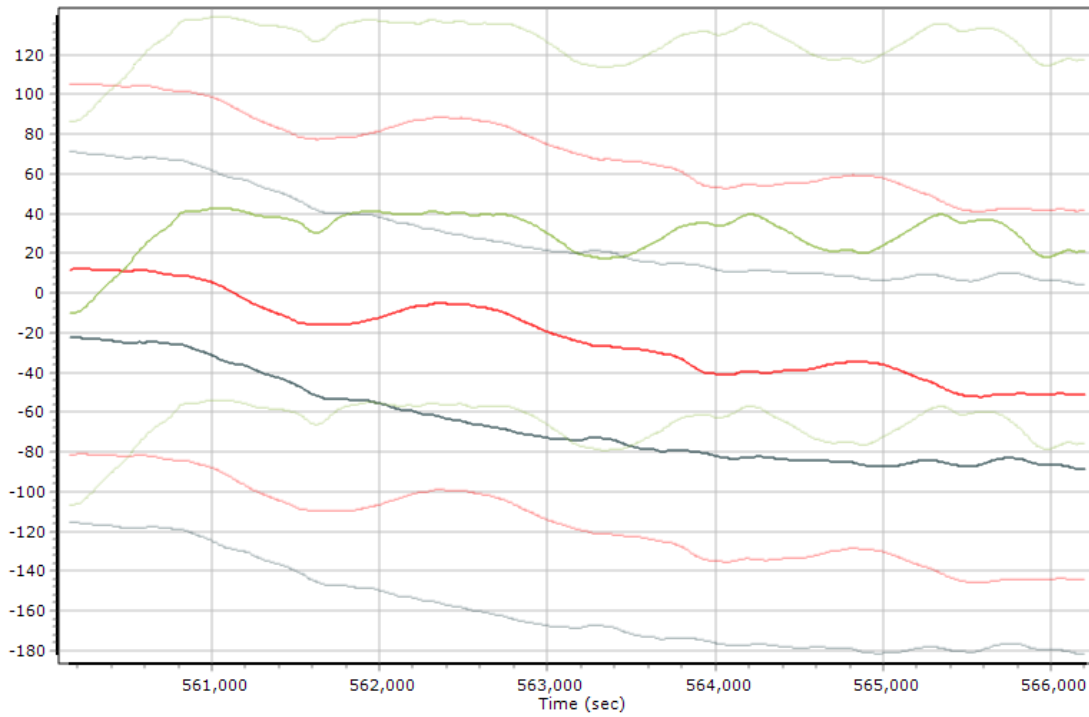
Processing mode



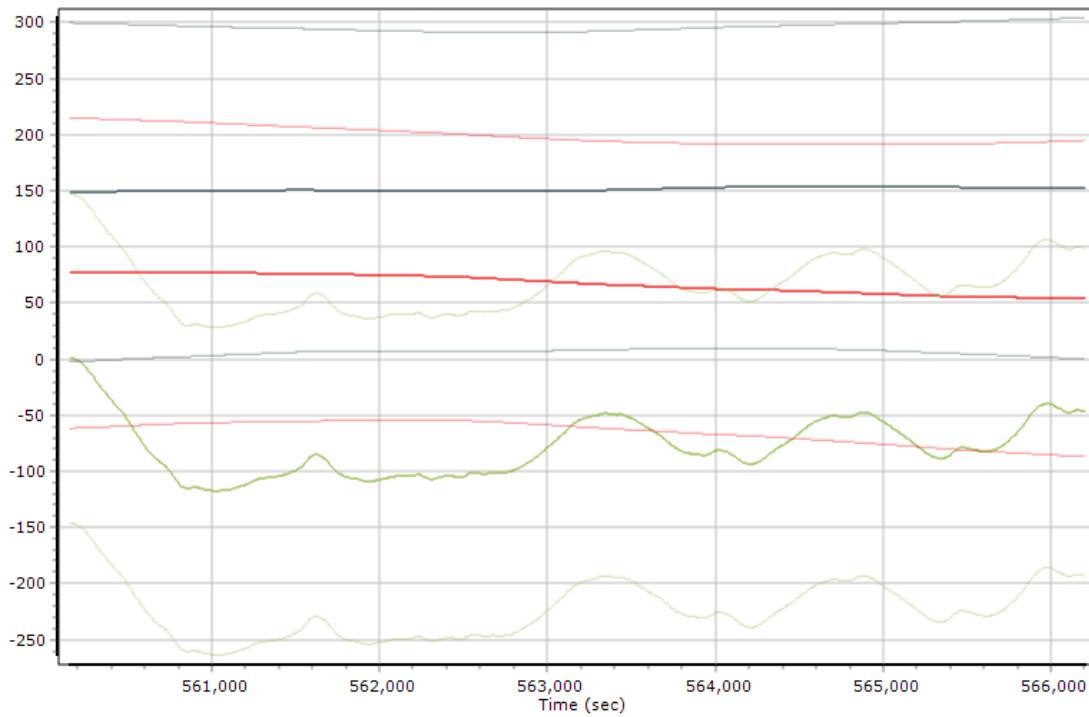
Forward Reverse

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

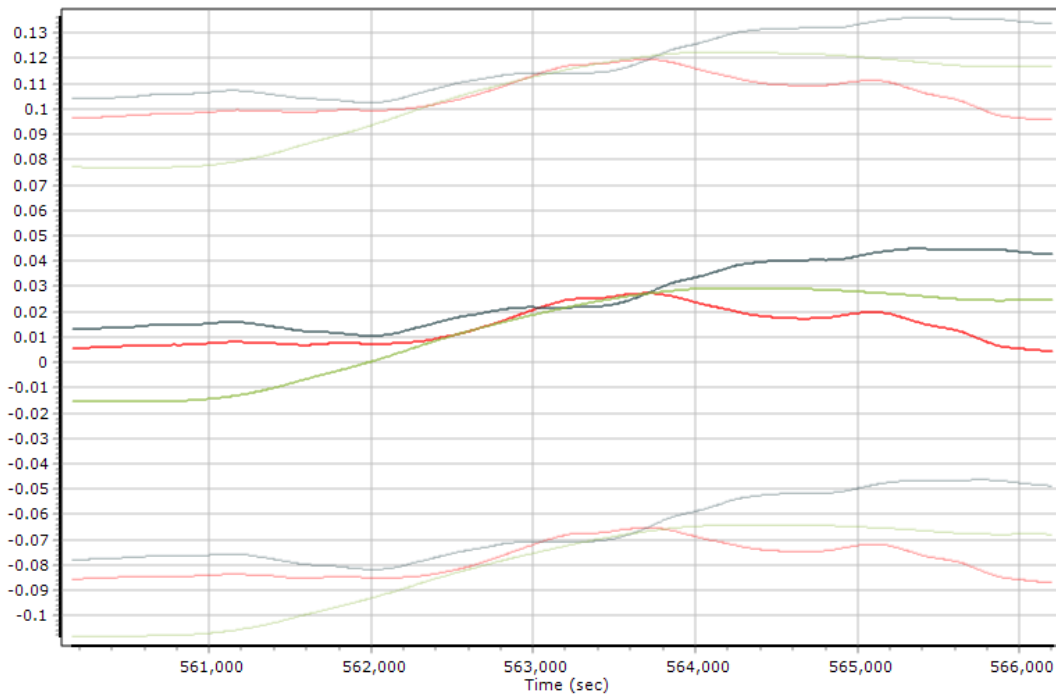
Sensor Errors



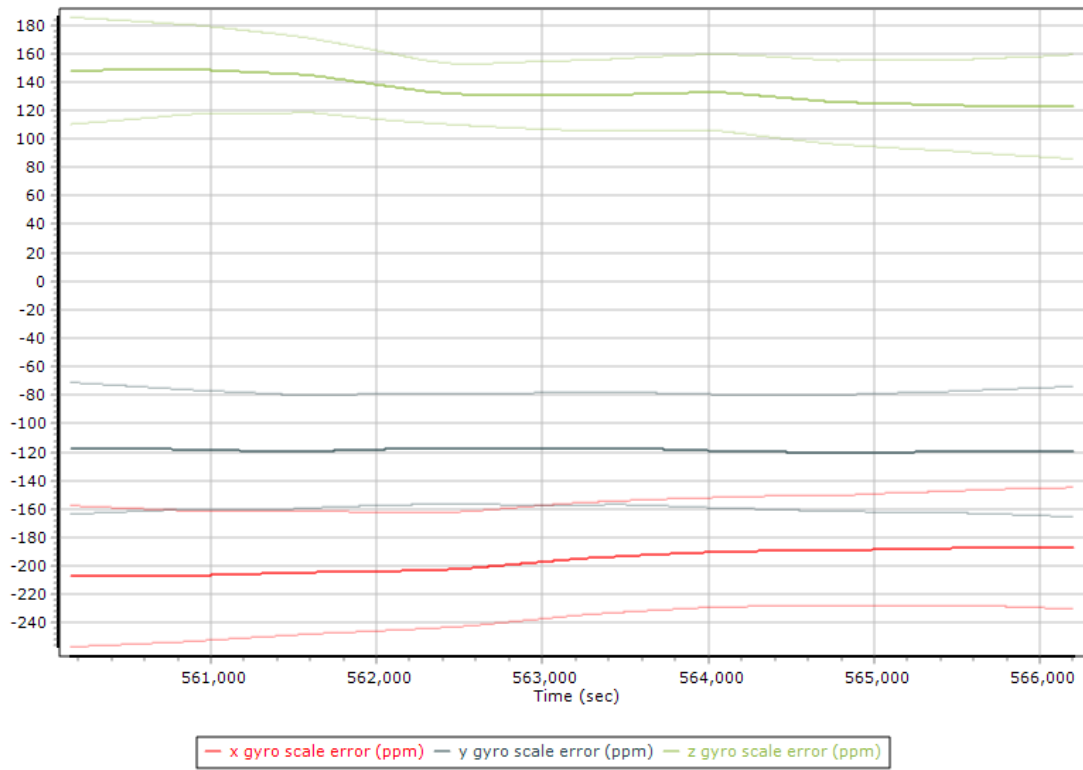
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



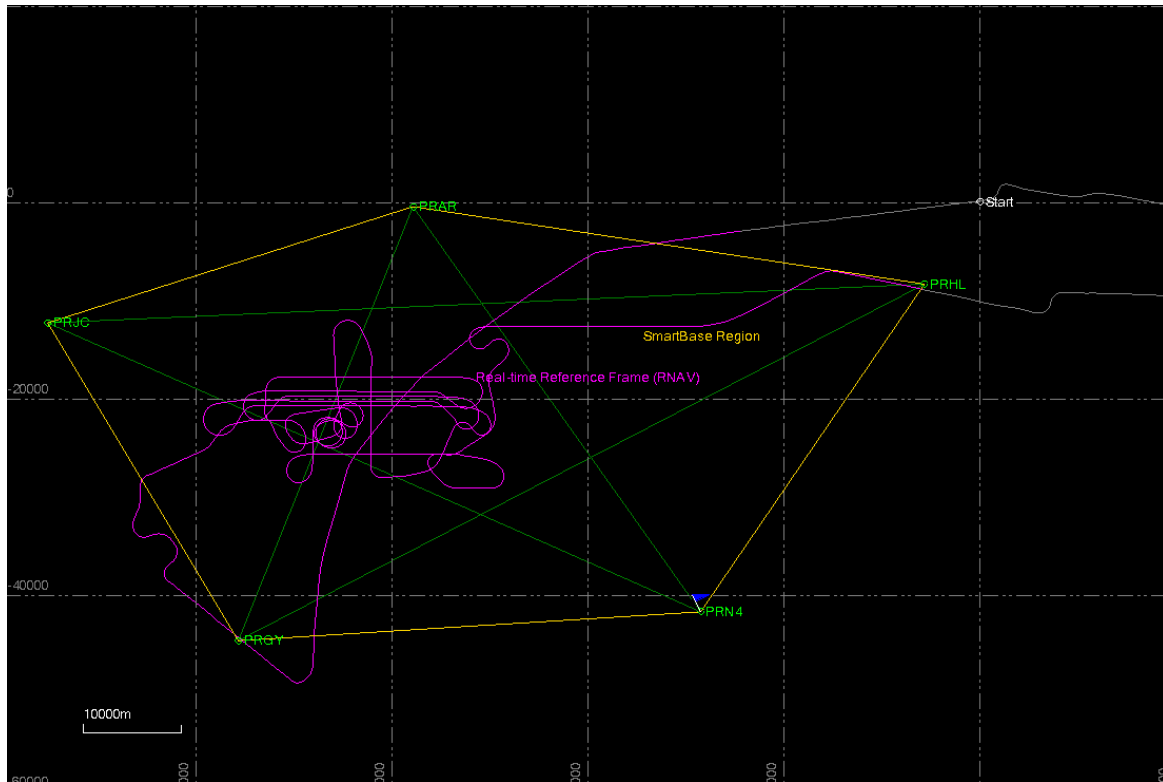
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



RBV18147A



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	-0.037 m	X	0.000 deg
Y	0.007 m	Y	0.000 deg
Z	-0.985 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

Timing

Start: 41152.981

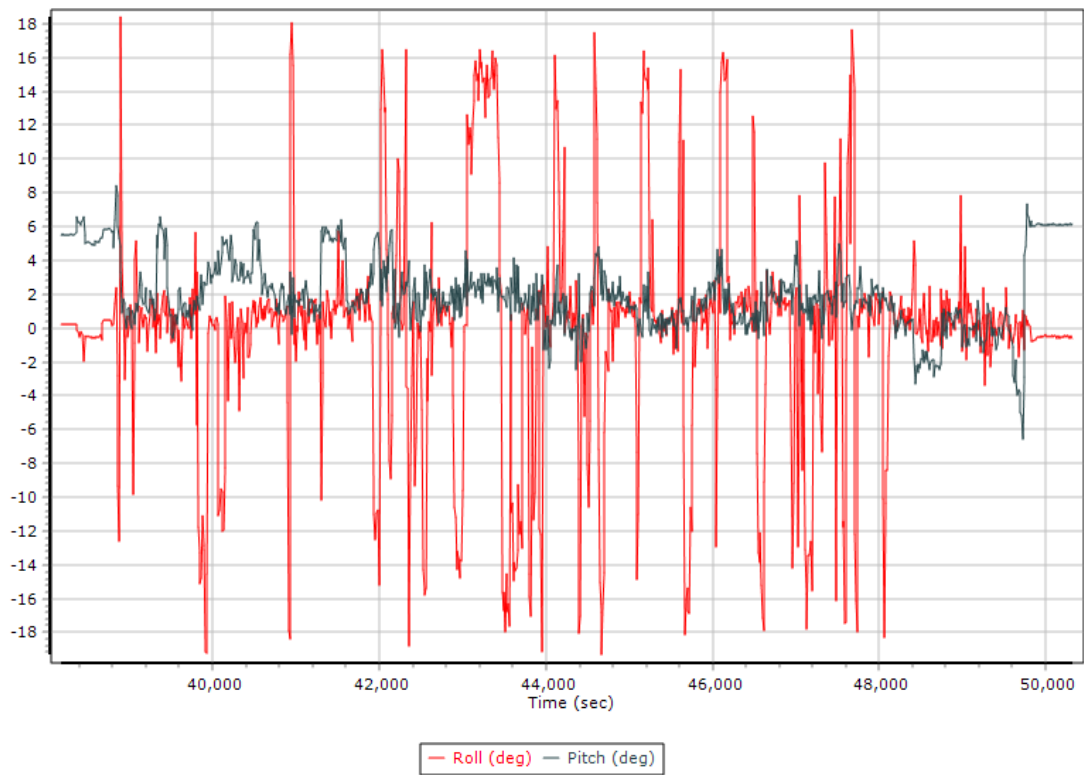
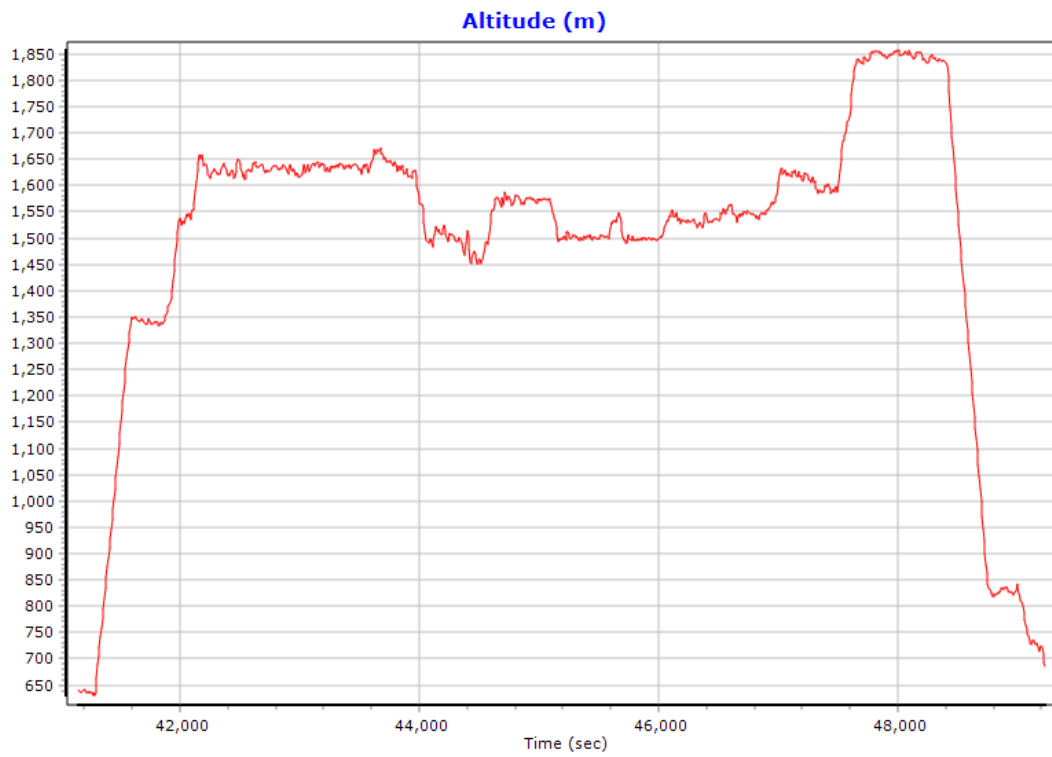
End: 49240.497

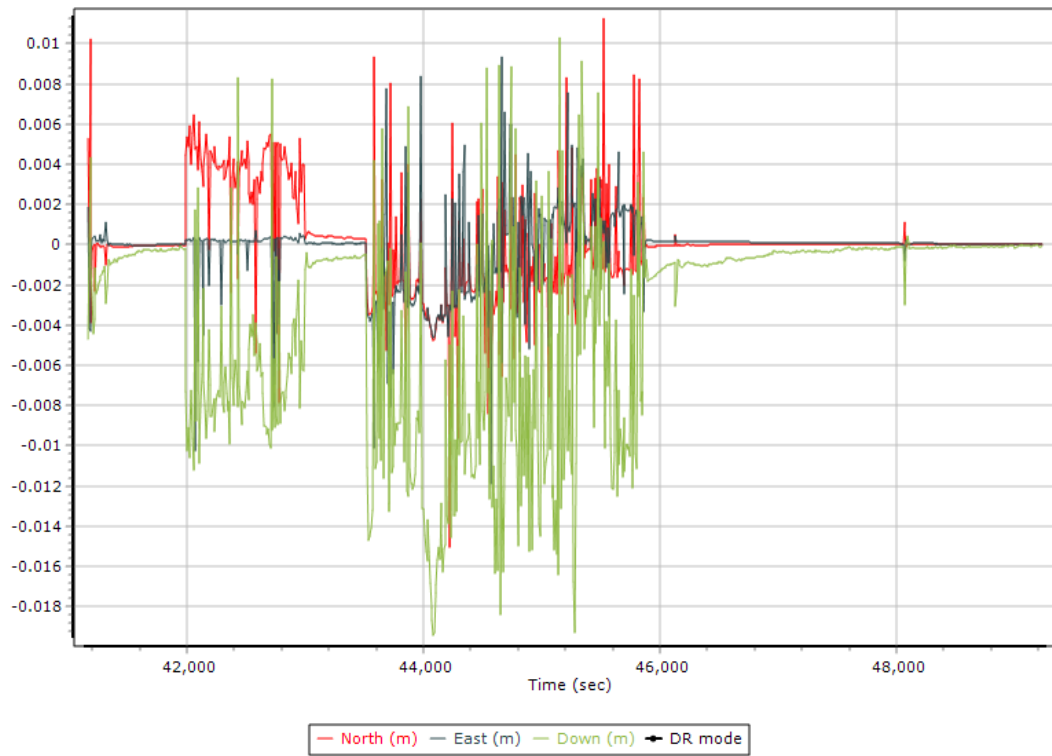
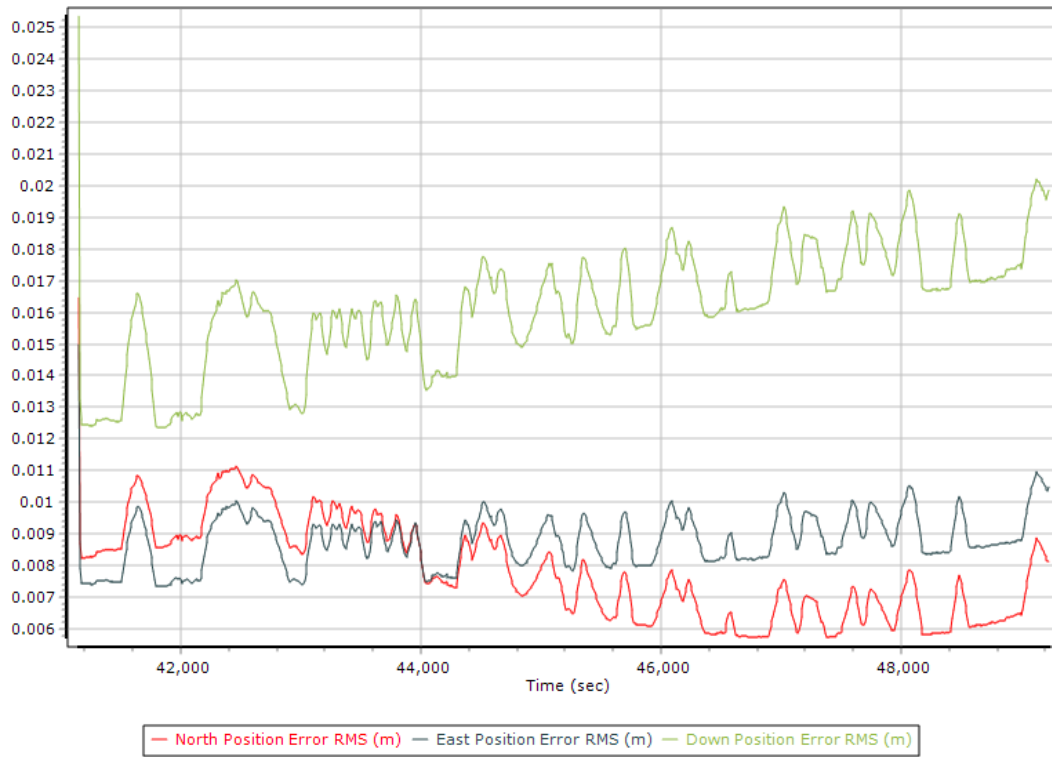
Entire time interval

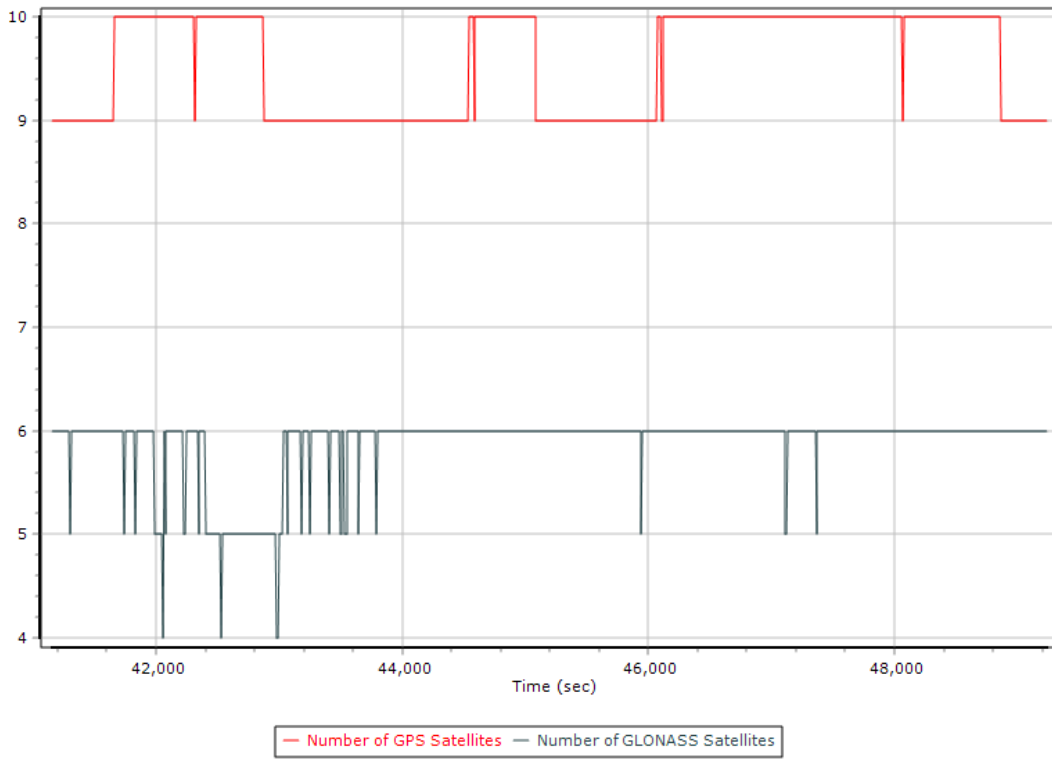
Seconds of start week

UTC Offset: 18.000

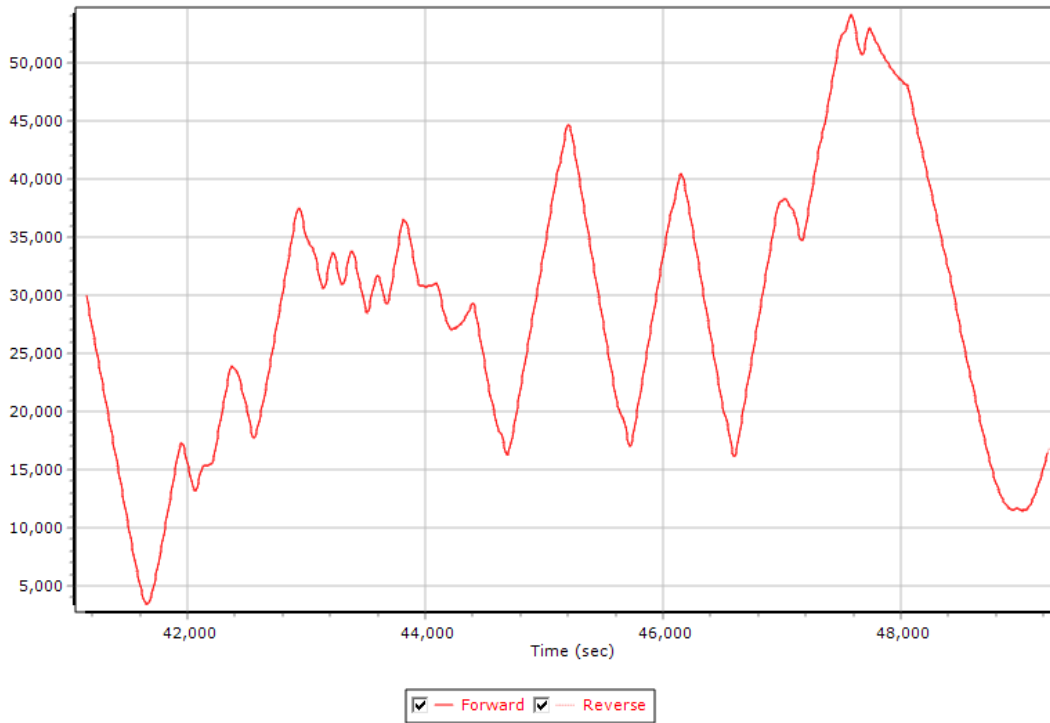
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



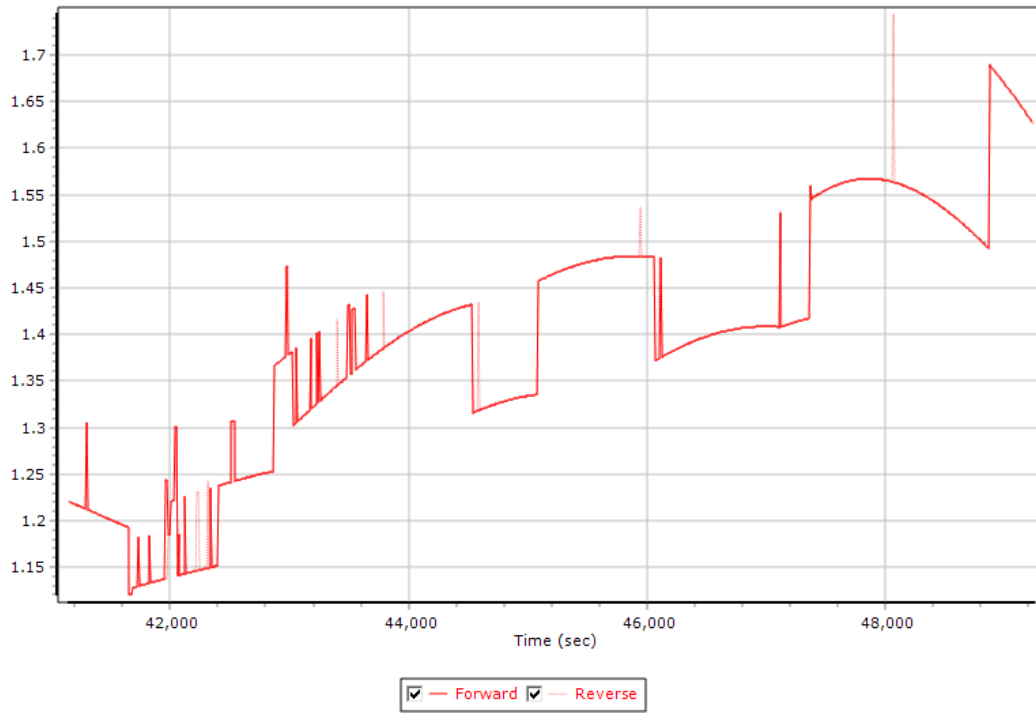




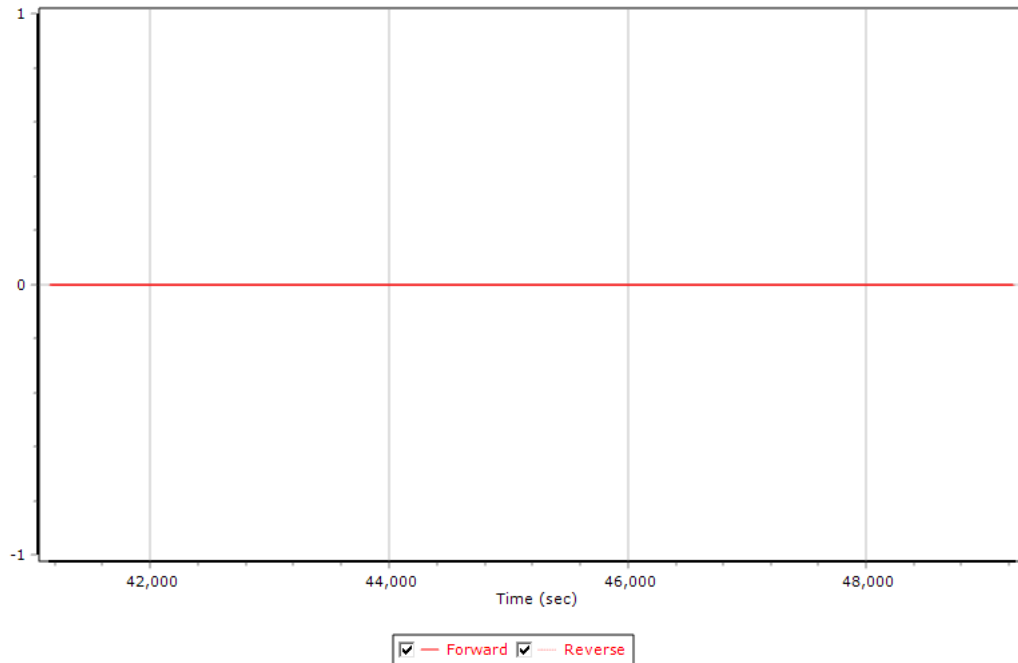
Baseline Length (m)



PDOP

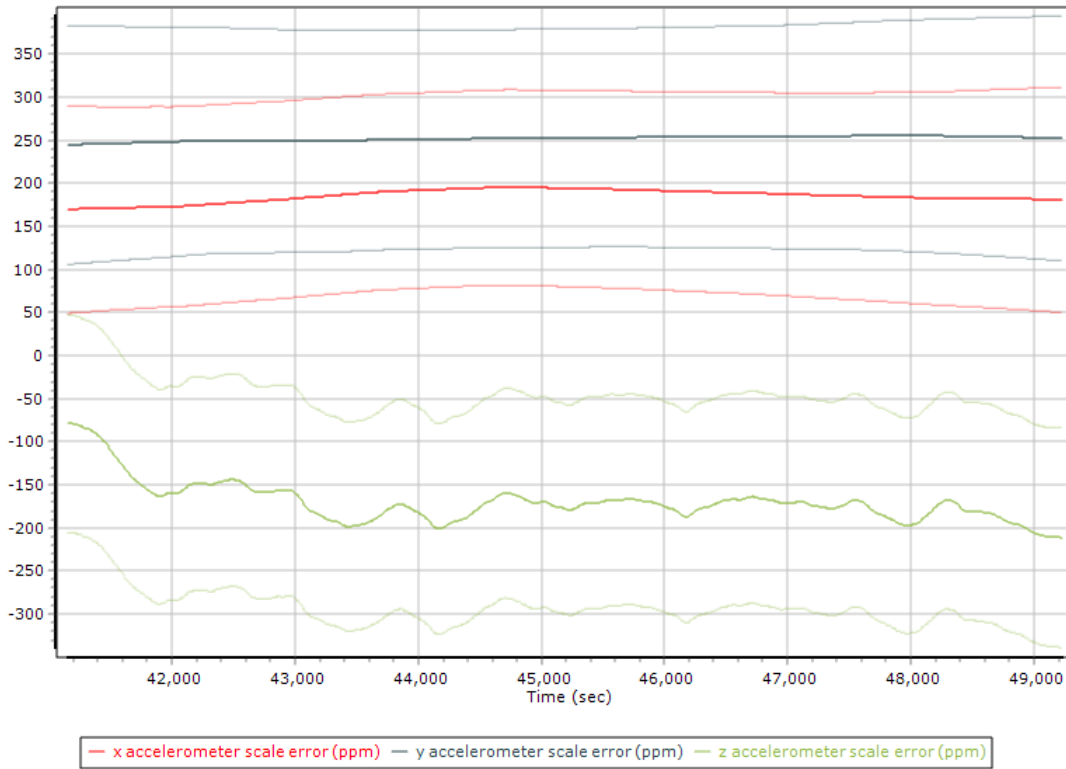
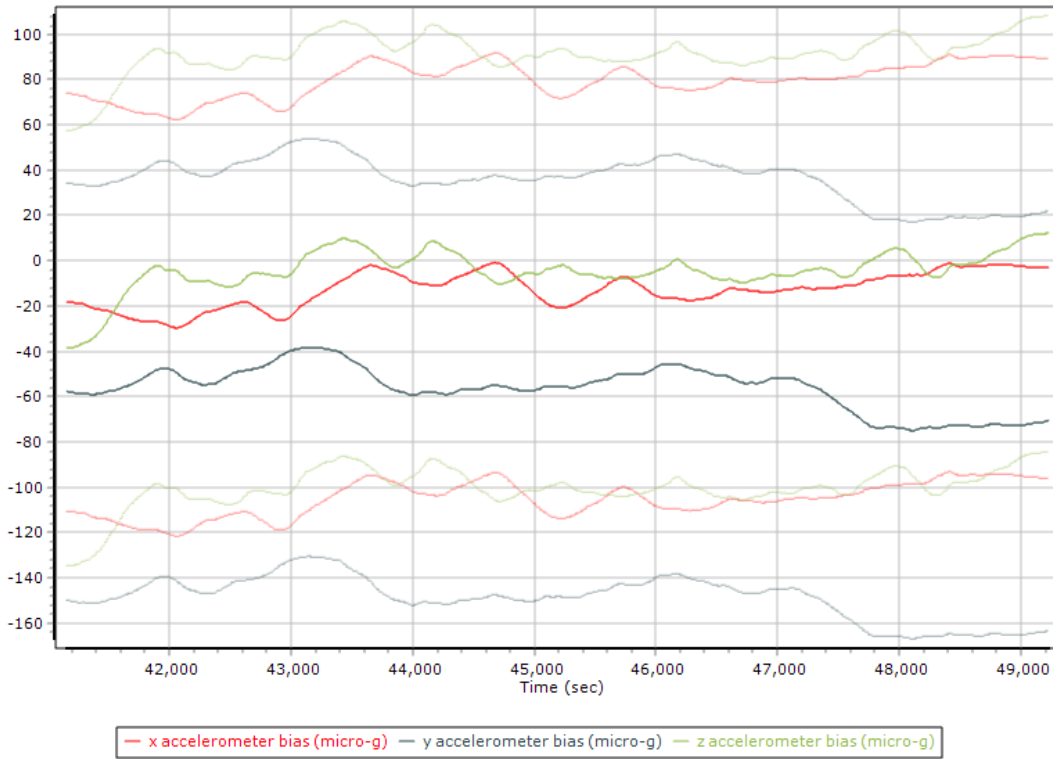


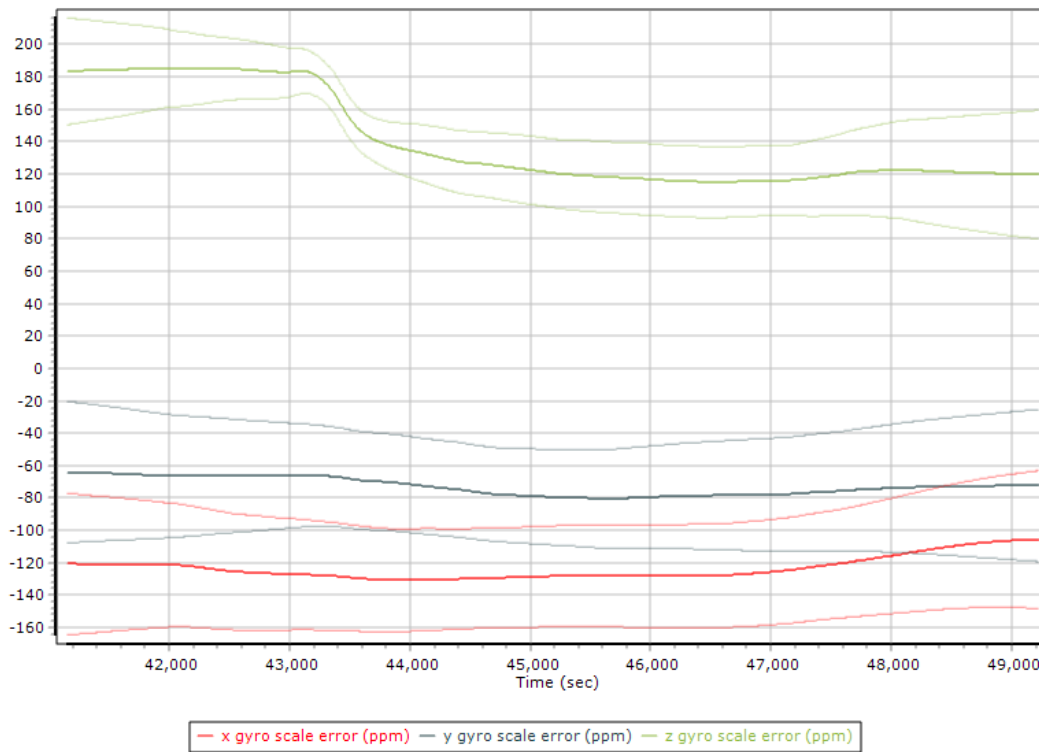
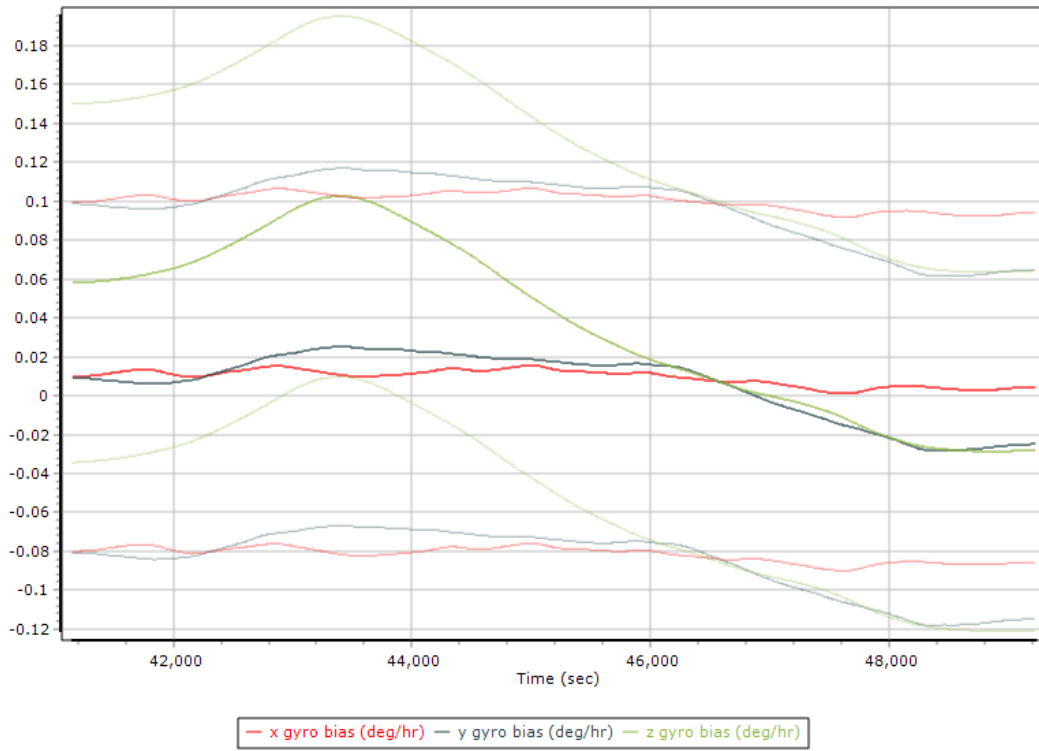
Processing mode



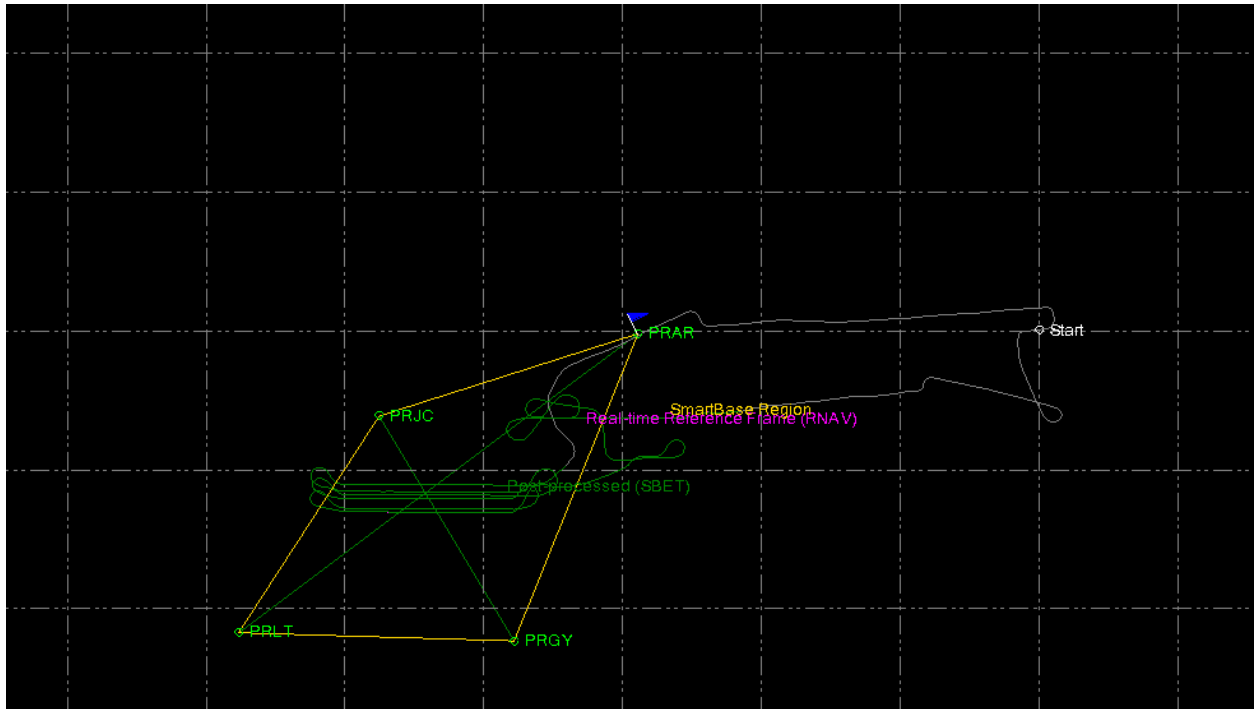
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





RBV18148A



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: -0.037 m	X: 0.000 deg
Y: 0.007 m	Y: 0.000 deg
Z: -0.985 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

Project Settings interface showing a sidebar menu and a main configuration panel.

Sidebar Menu:

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

Main Configuration Panel:

Timing

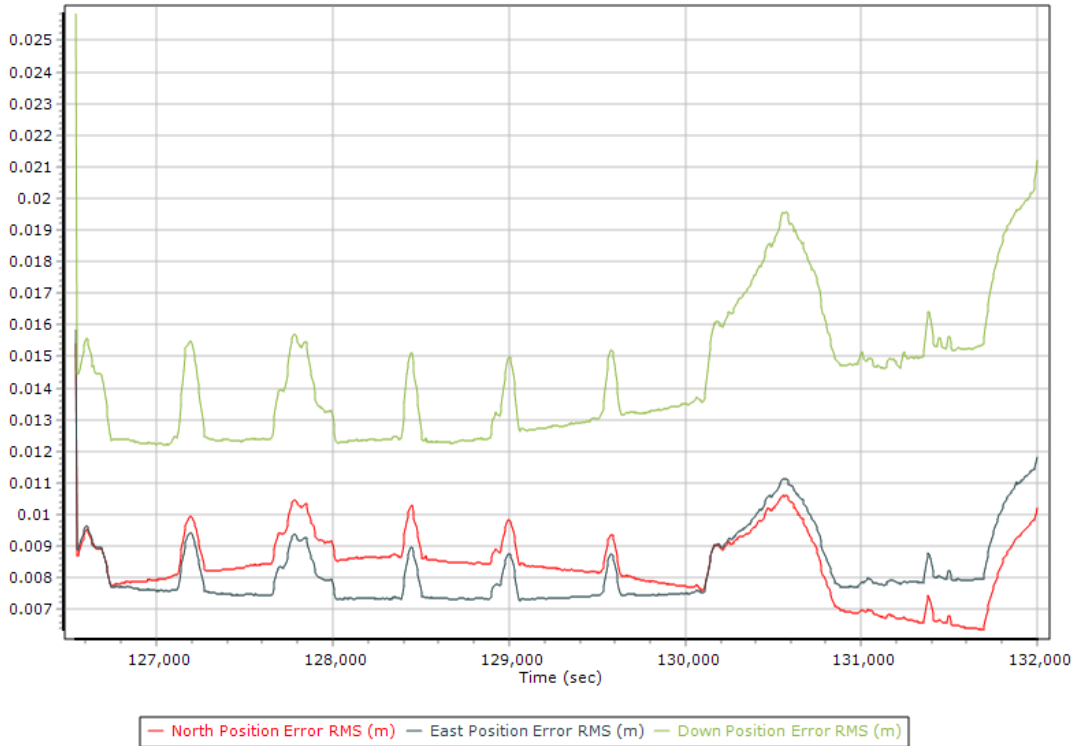
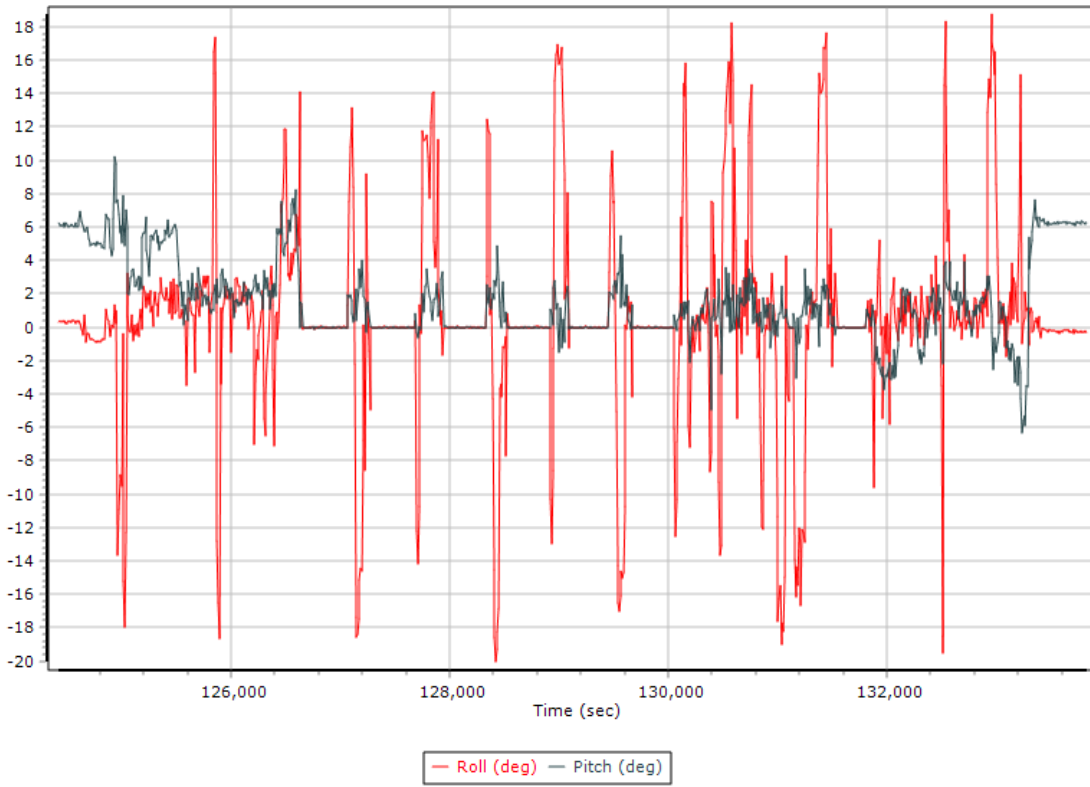
Start: 126536.128
End: 132008.409

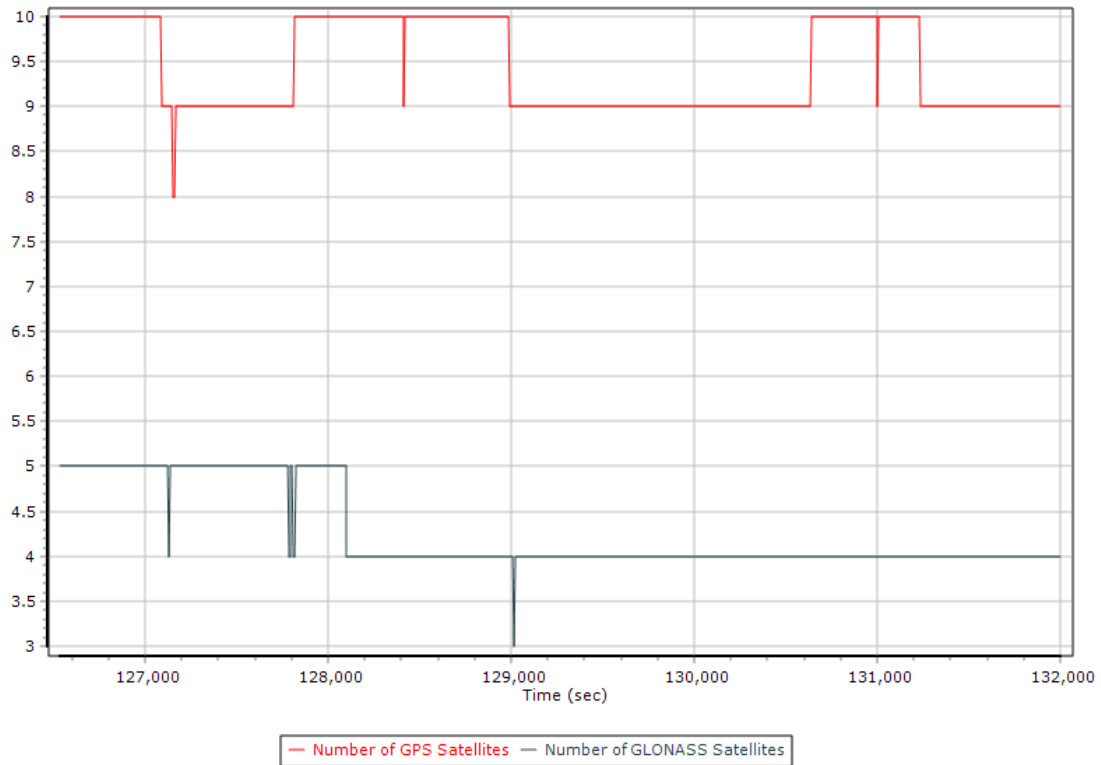
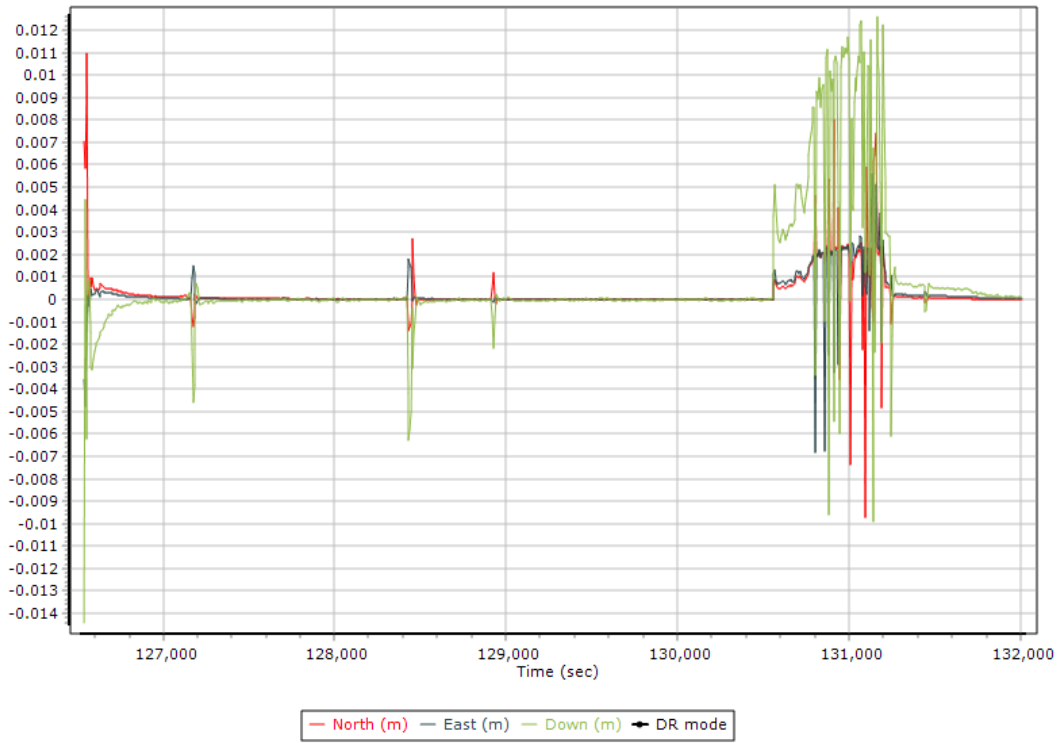
Entire time interval
 Seconds of start week

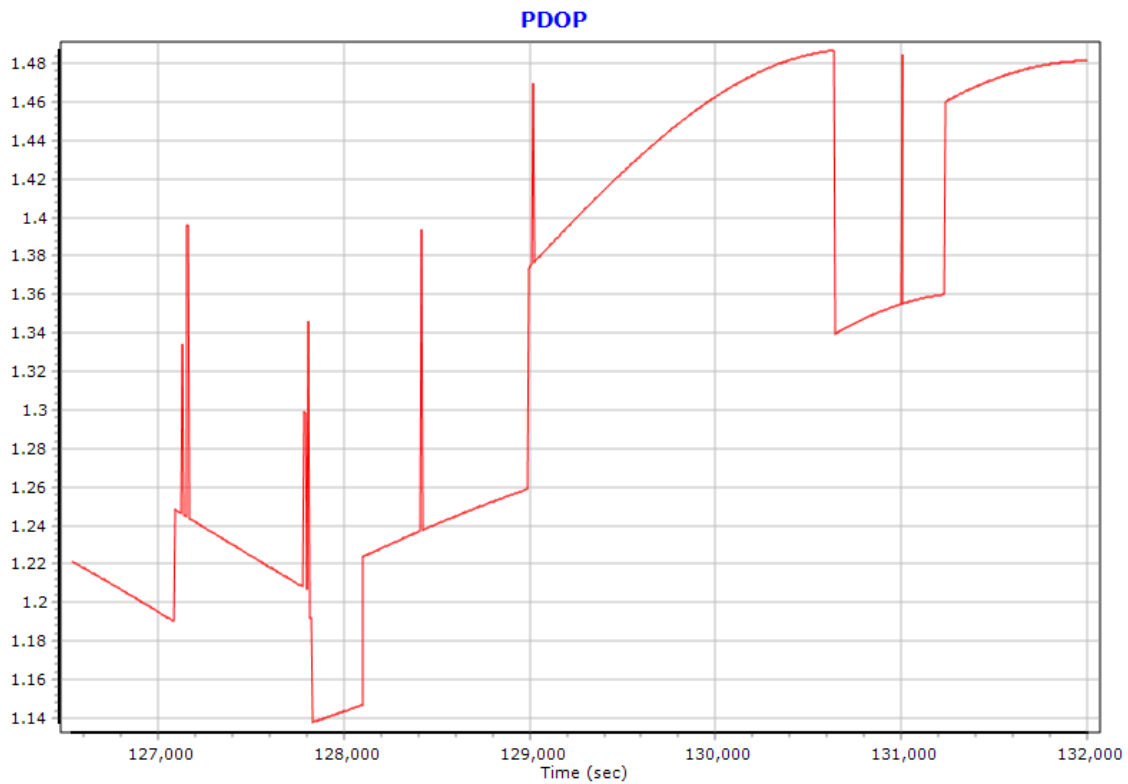
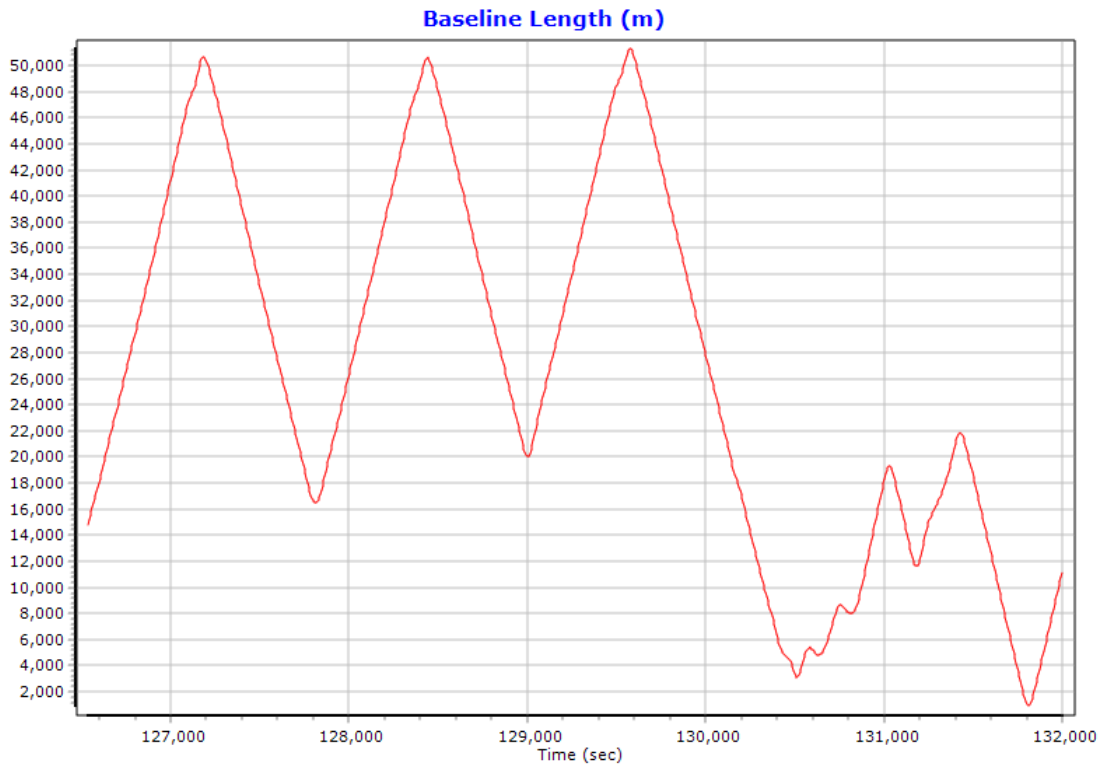
UTC Offset: 18.000

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

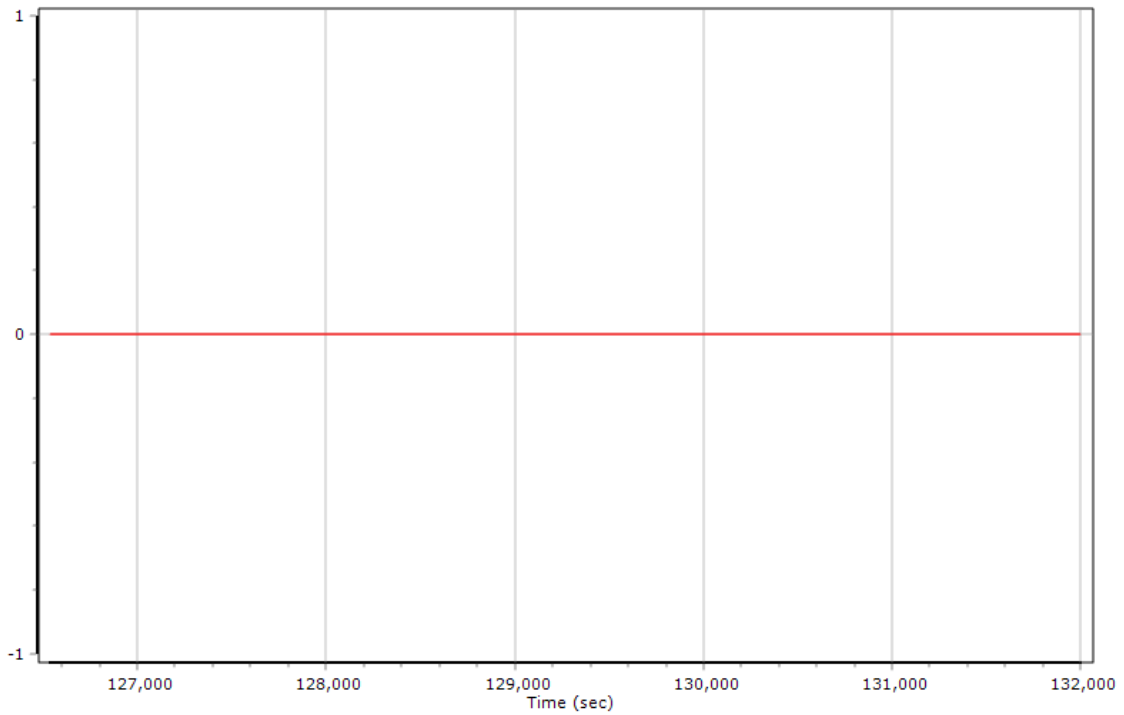






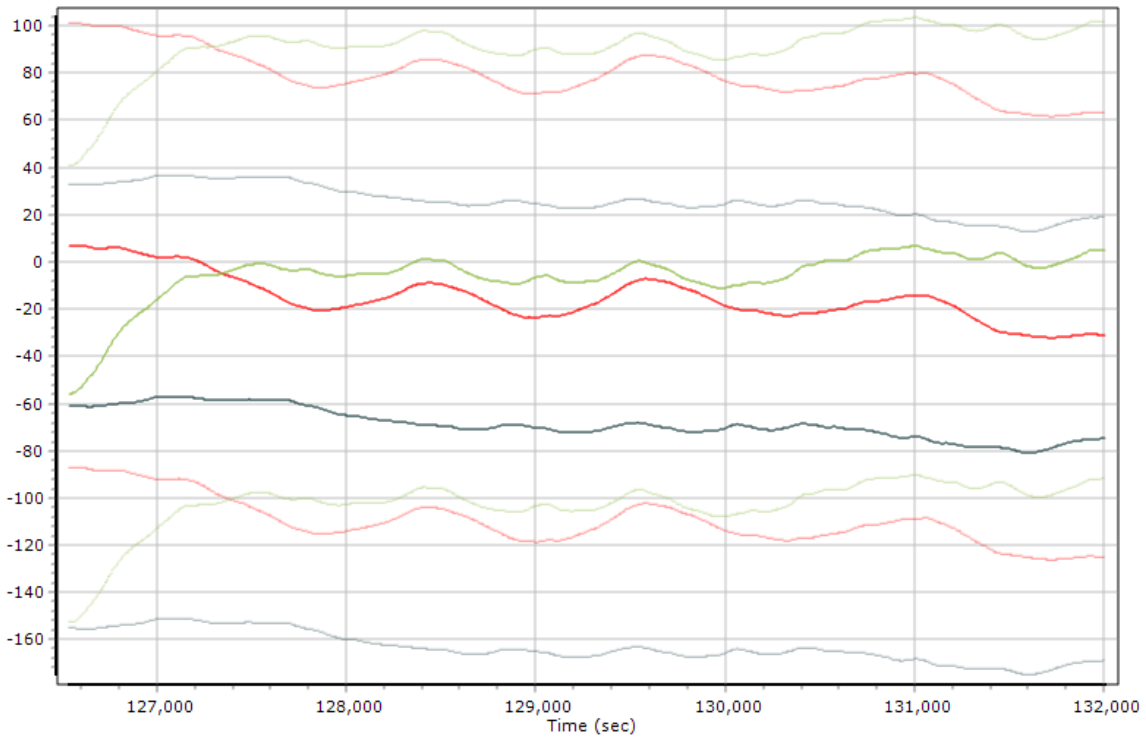


Processing mode

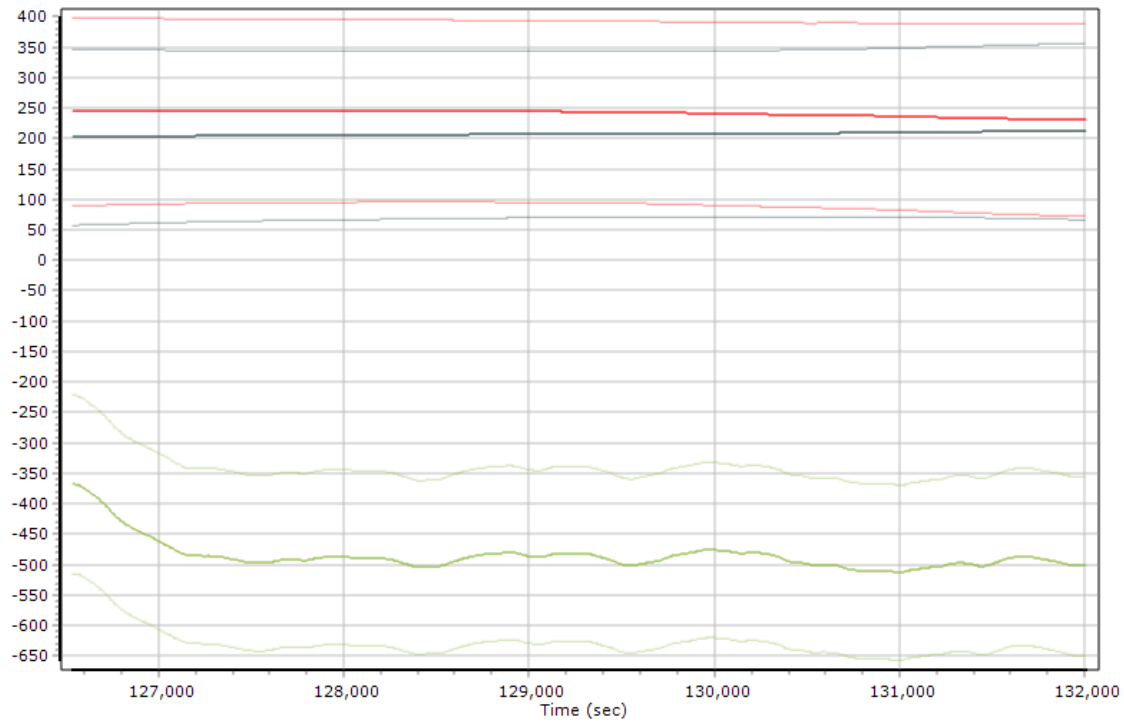


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

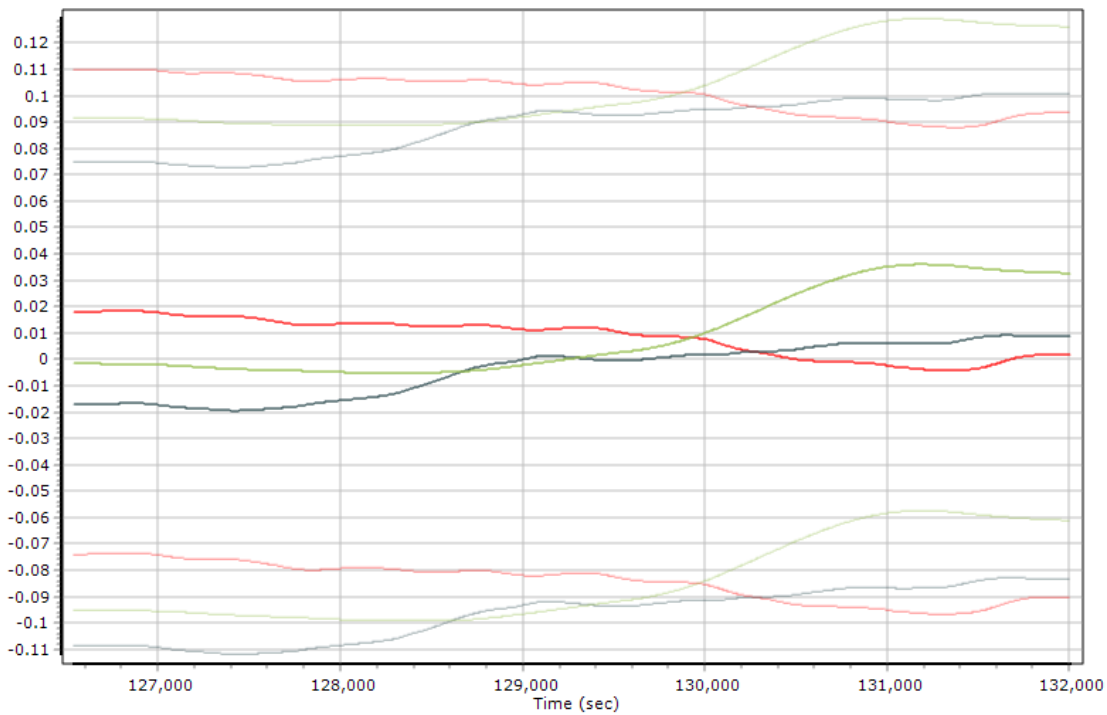
Sensor Errors



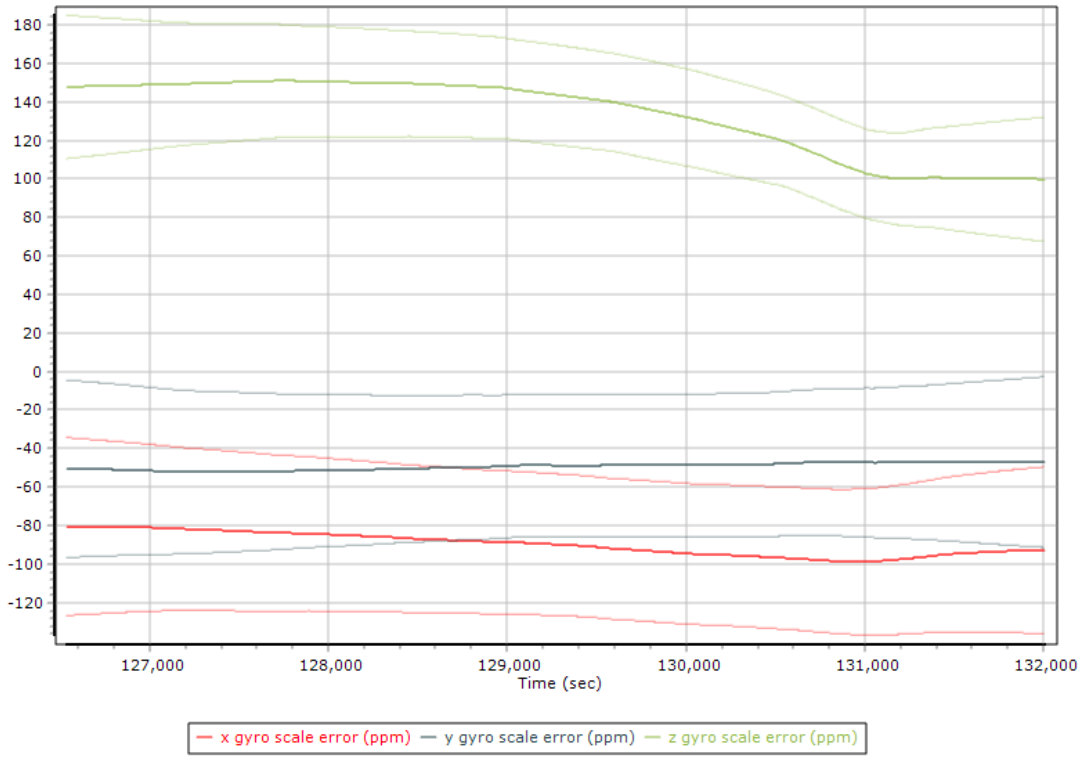
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



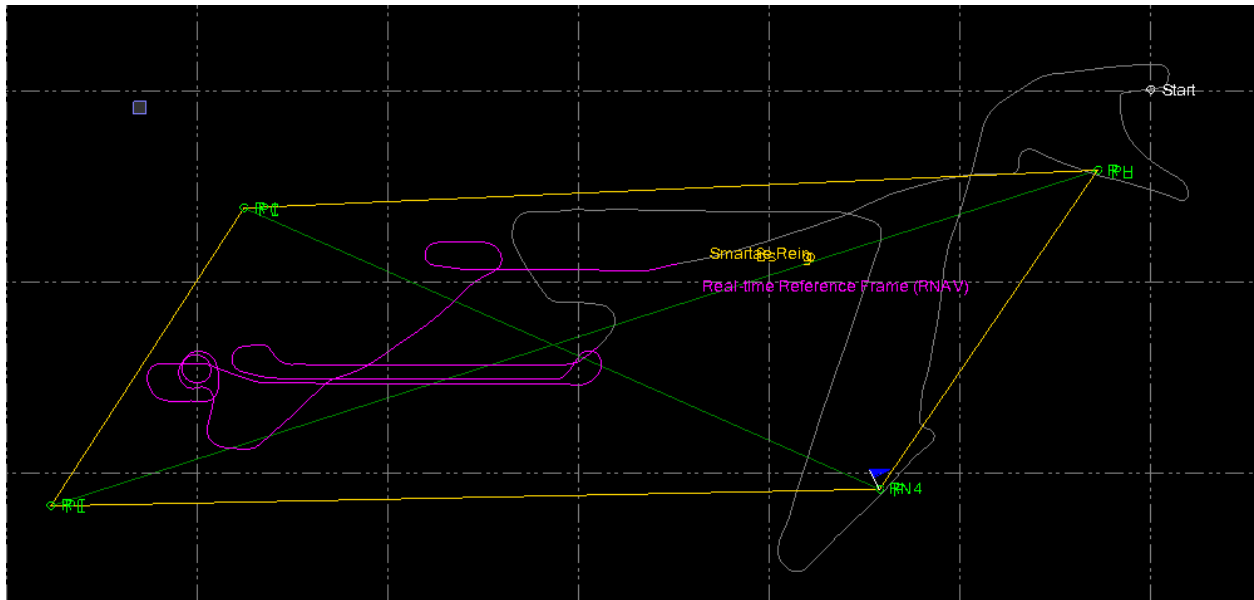
x accelerometer scale error (ppm) y accelerometer scale error (ppm) z accelerometer scale error (ppm)

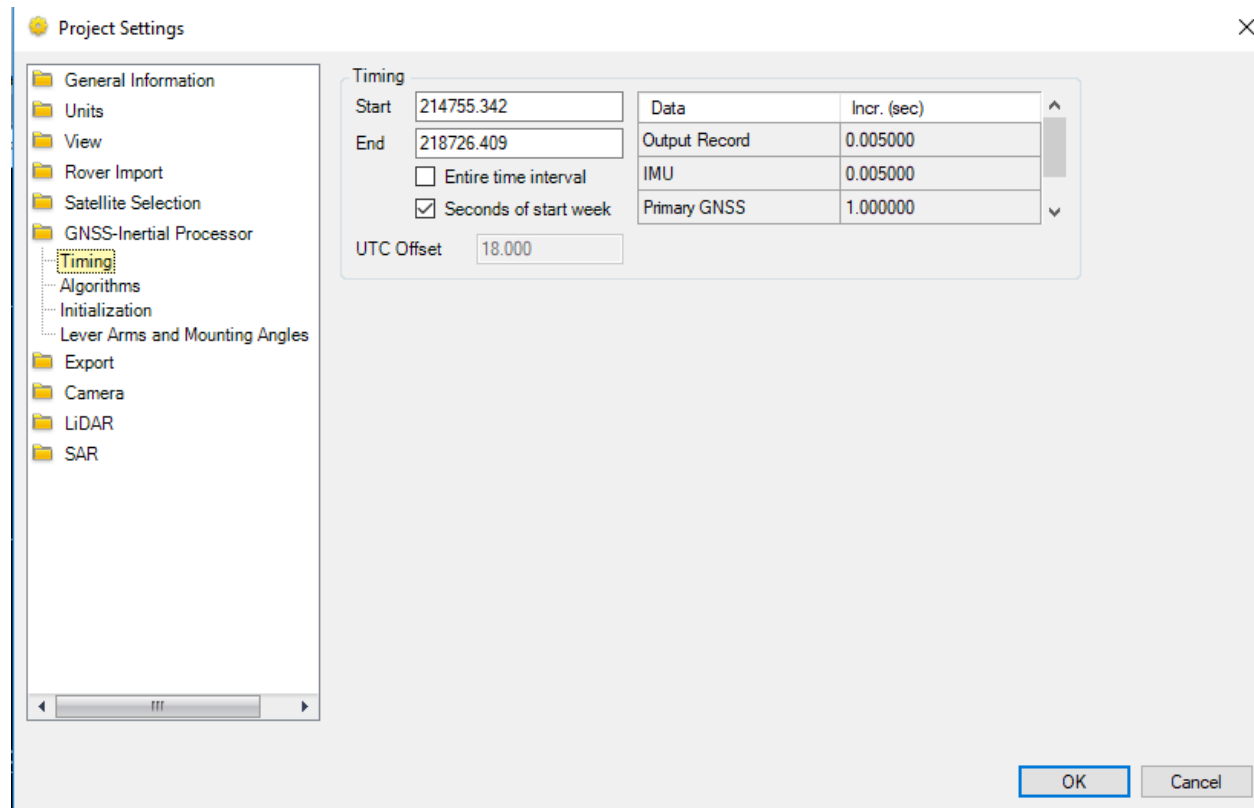
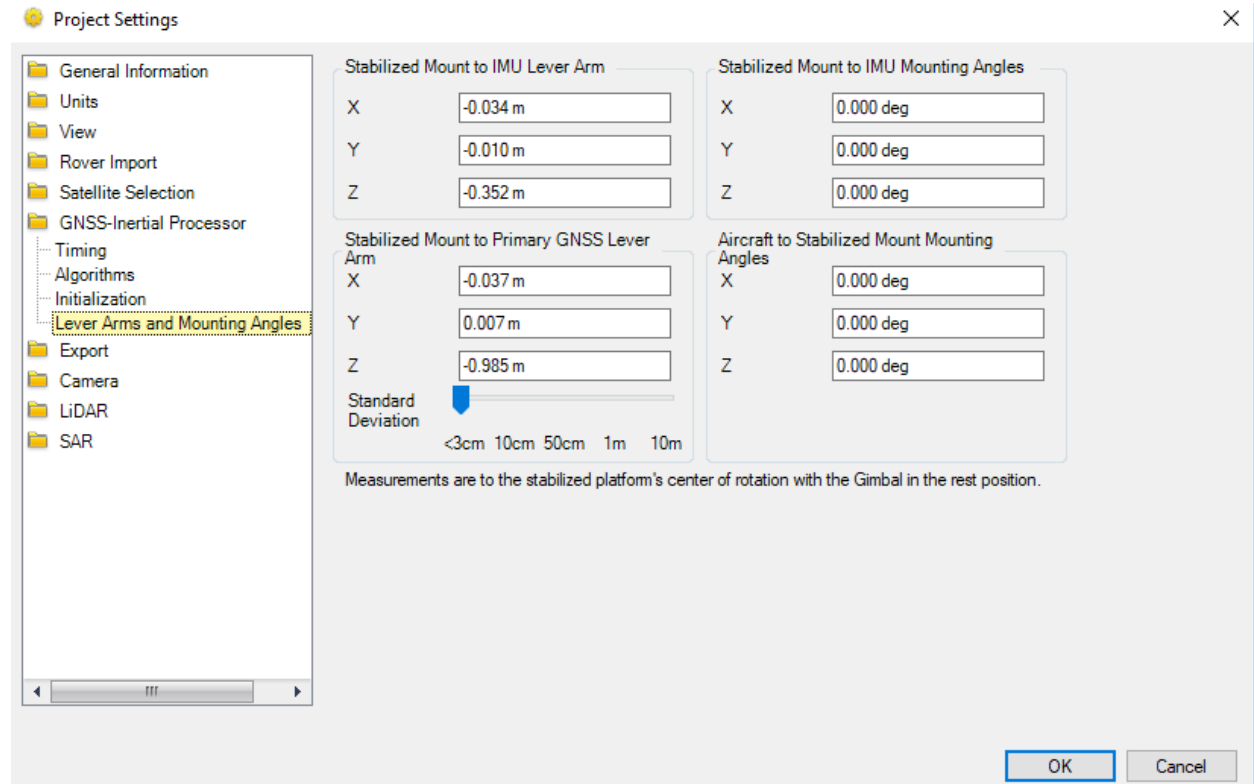


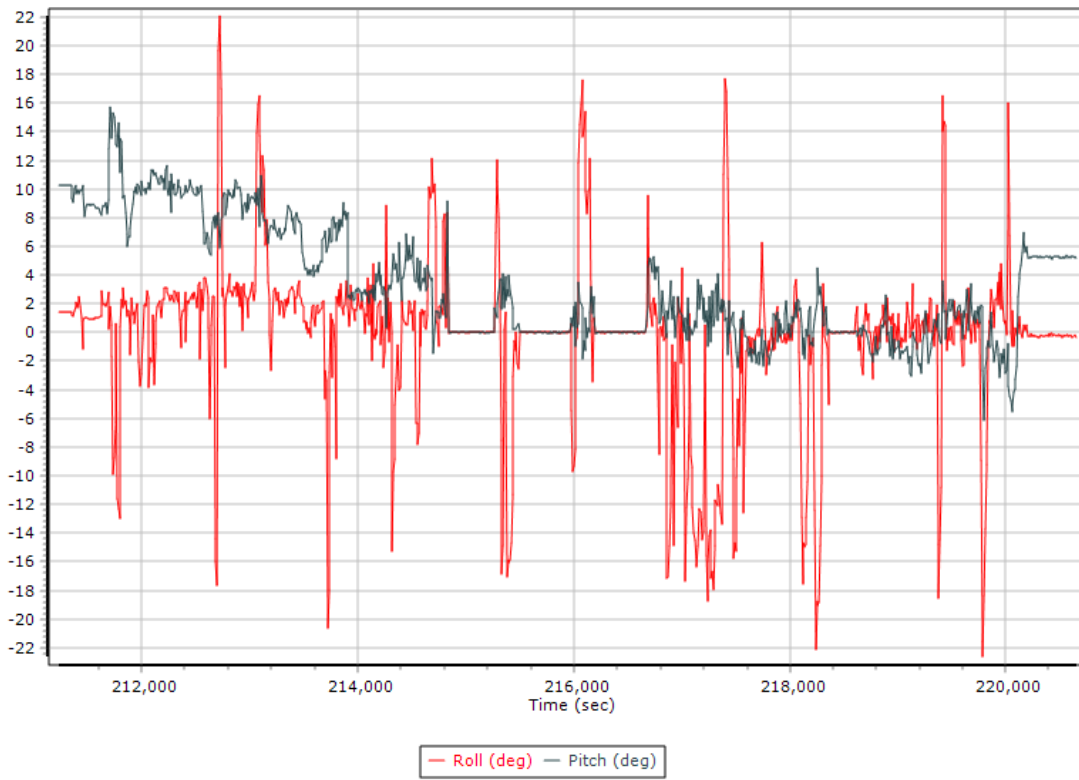
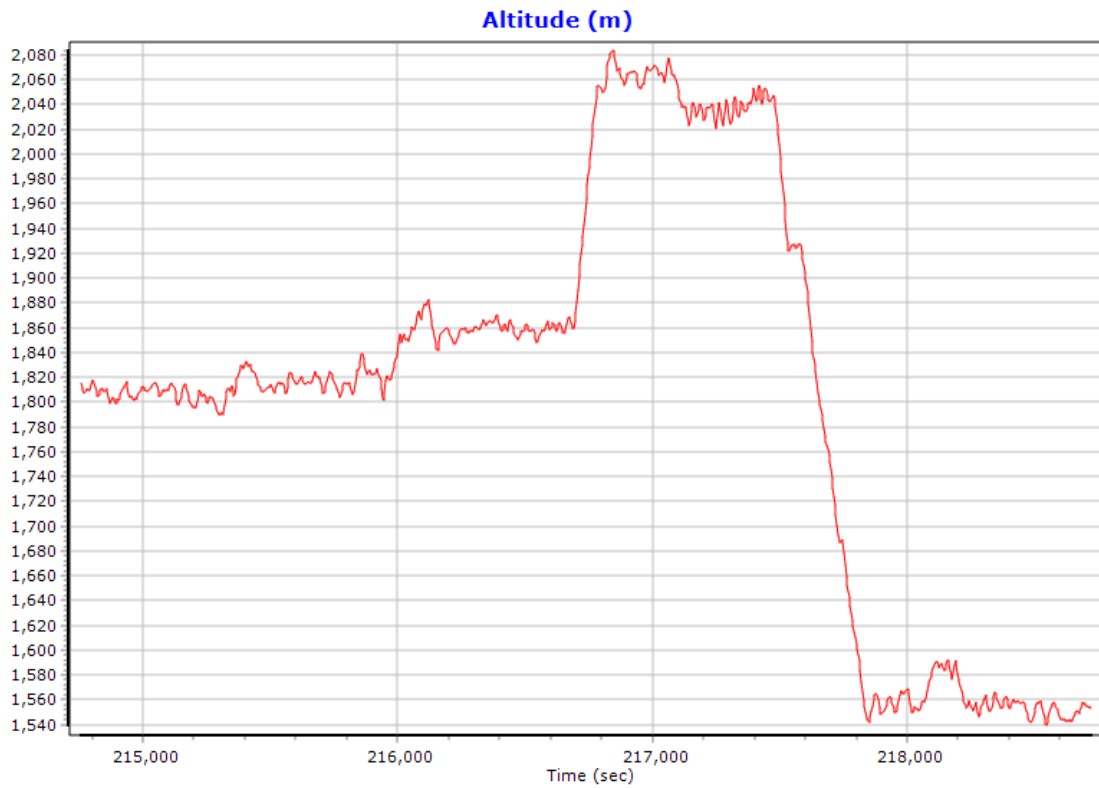
x gyro bias (deg/hr) y gyro bias (deg/hr) z gyro bias (deg/hr)

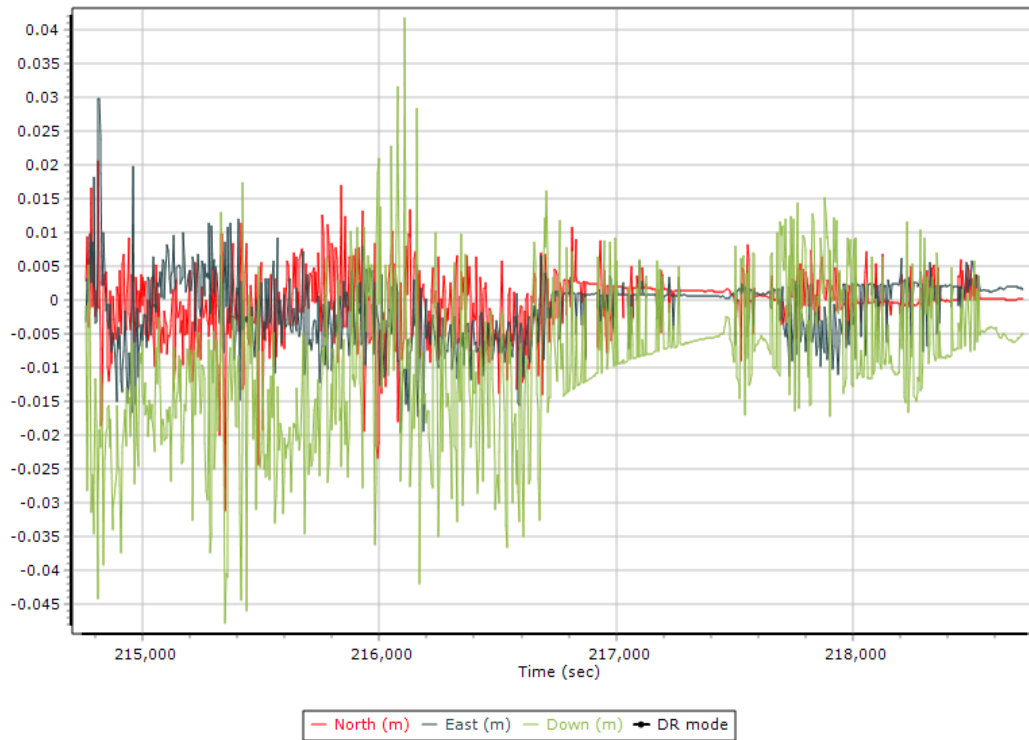
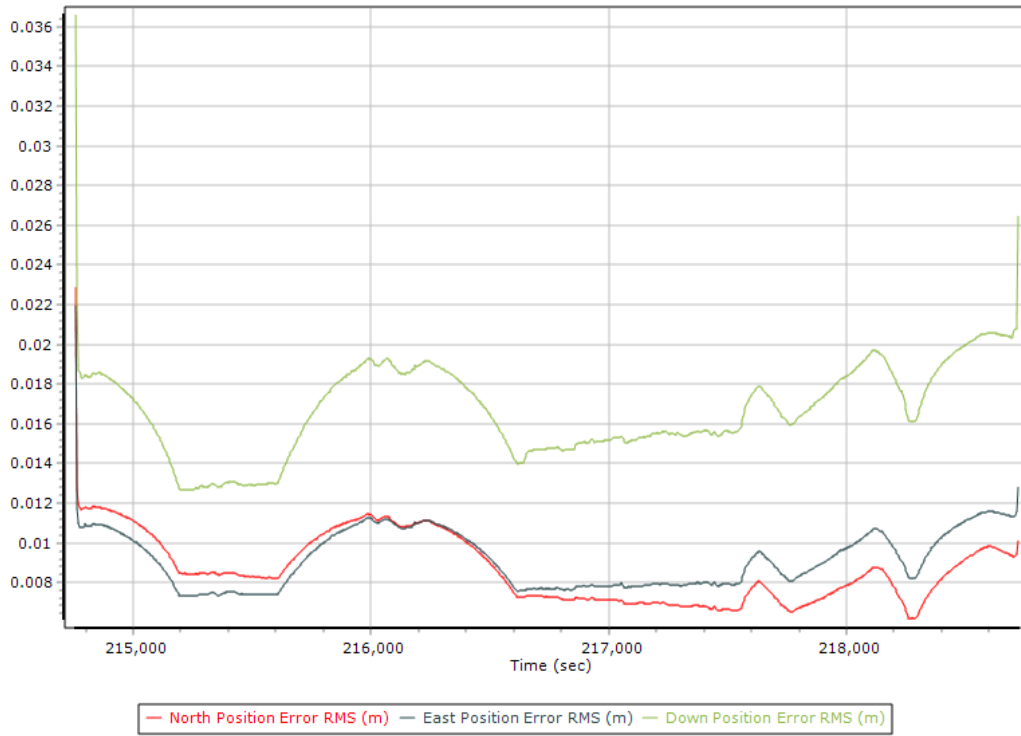


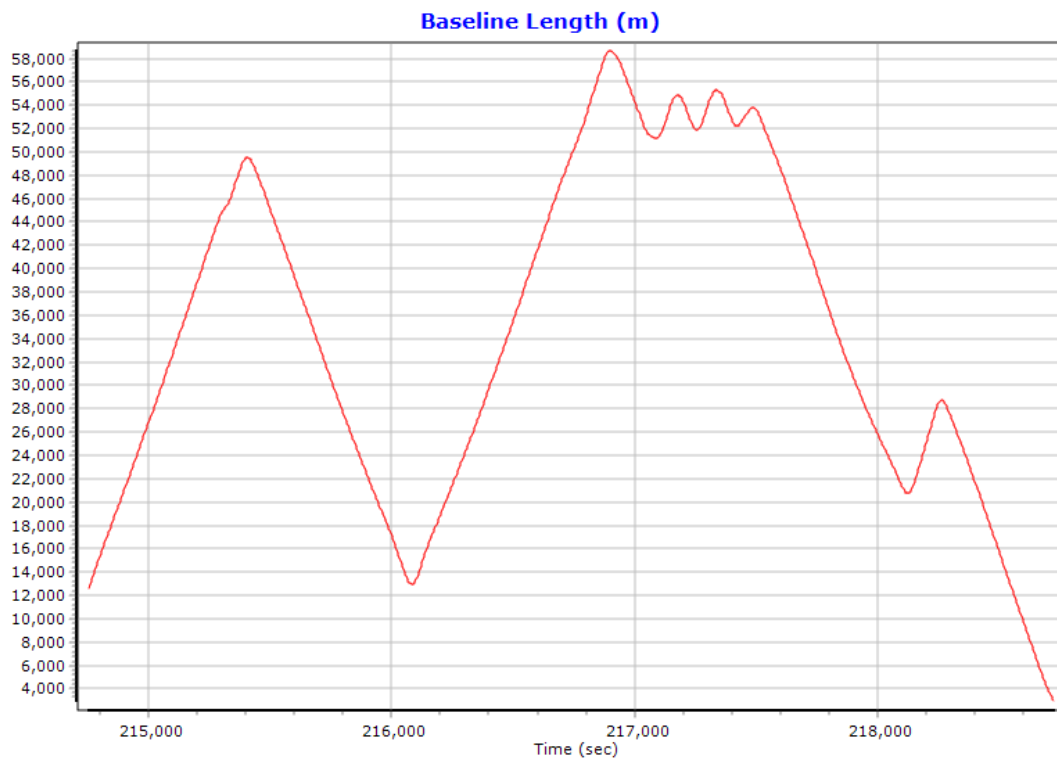
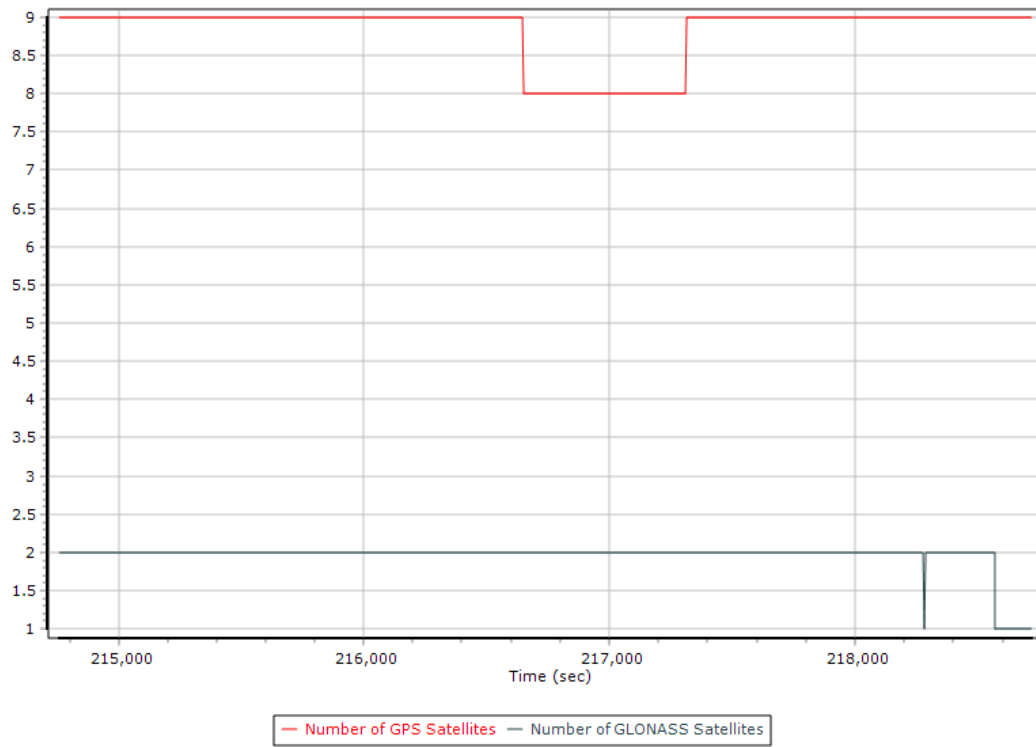
RBV18149A

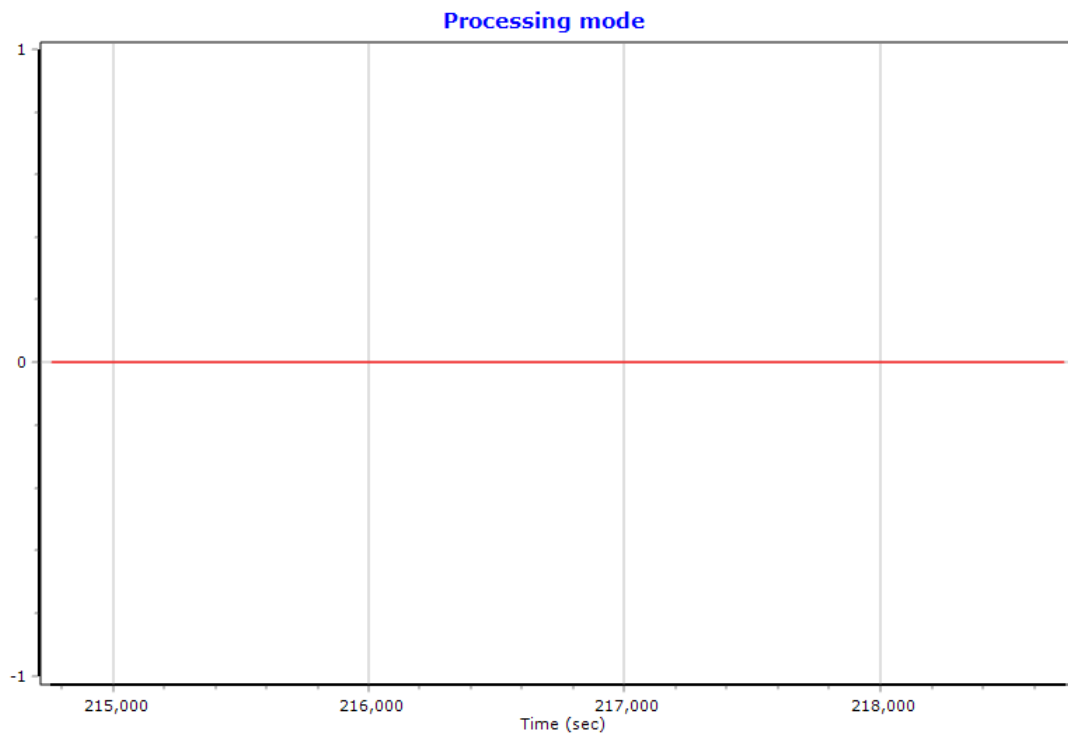
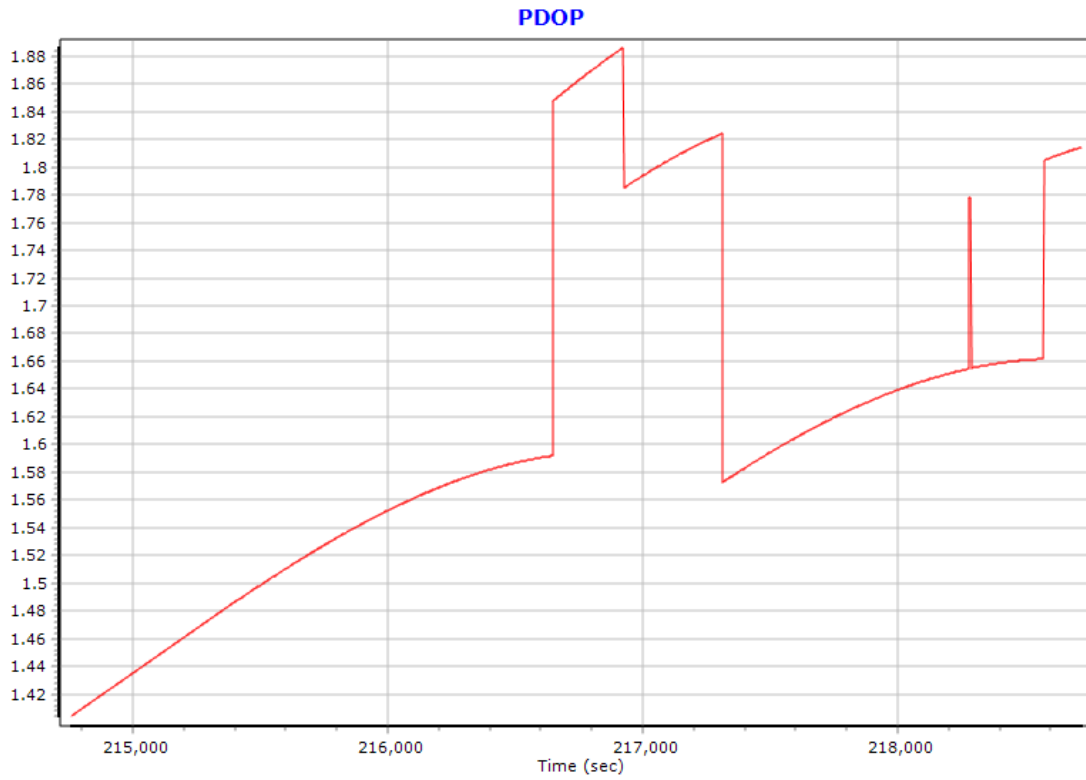






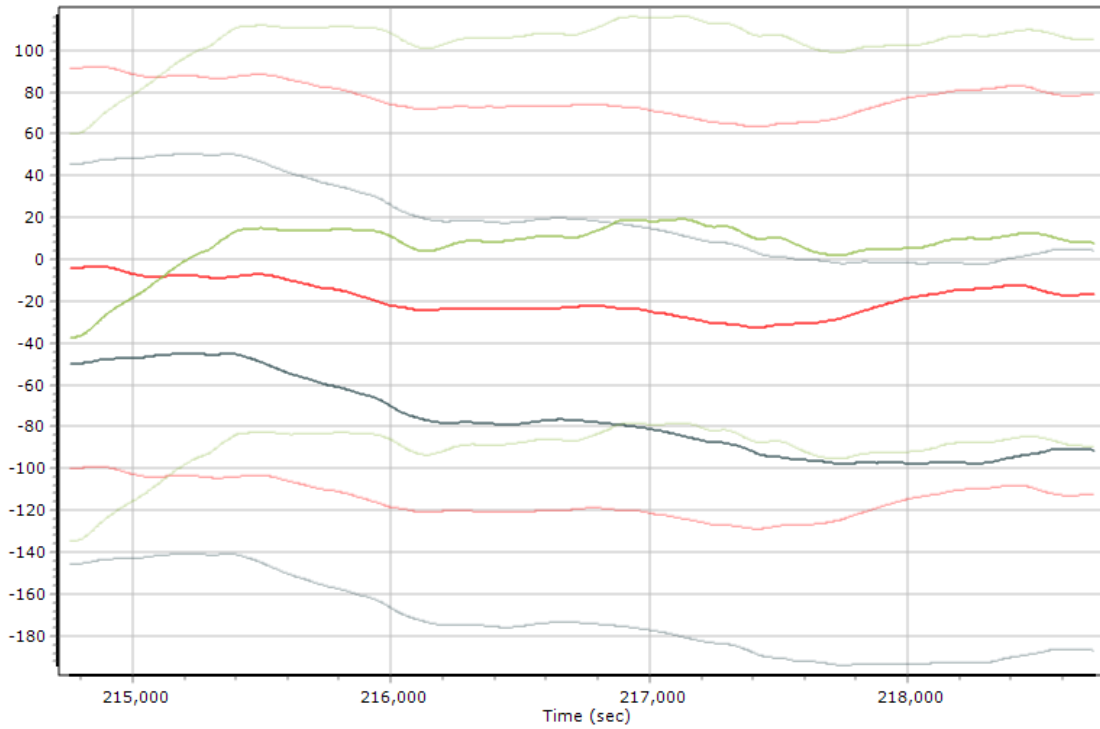




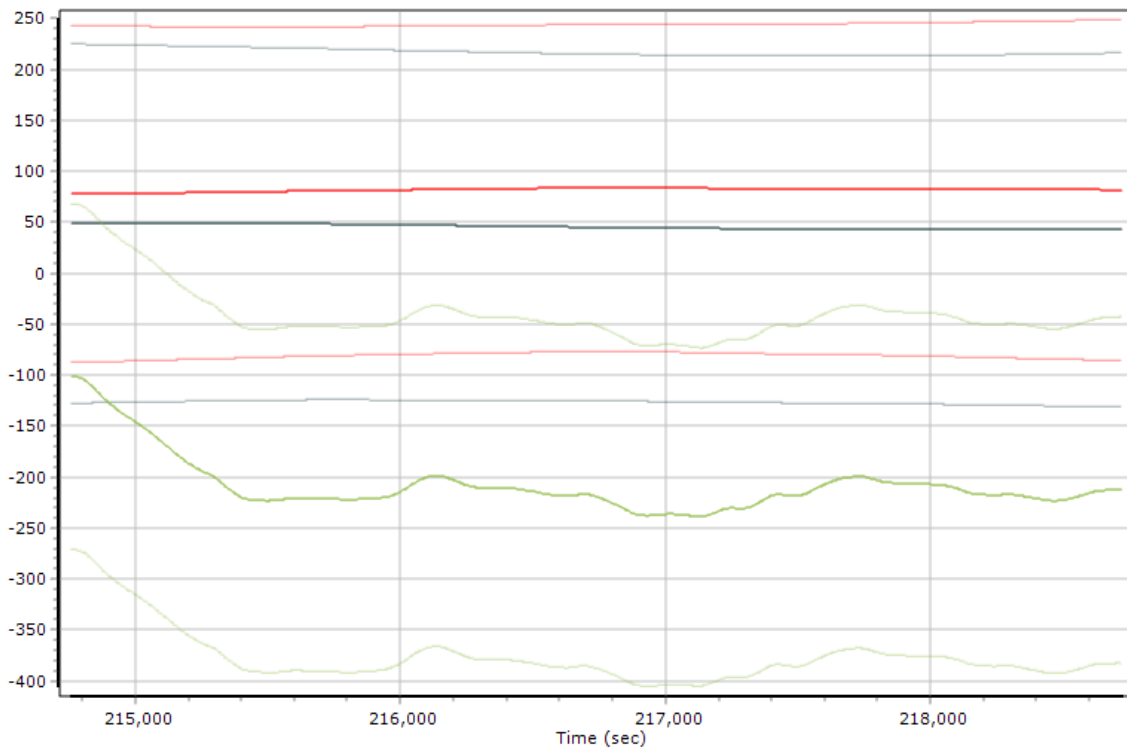


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

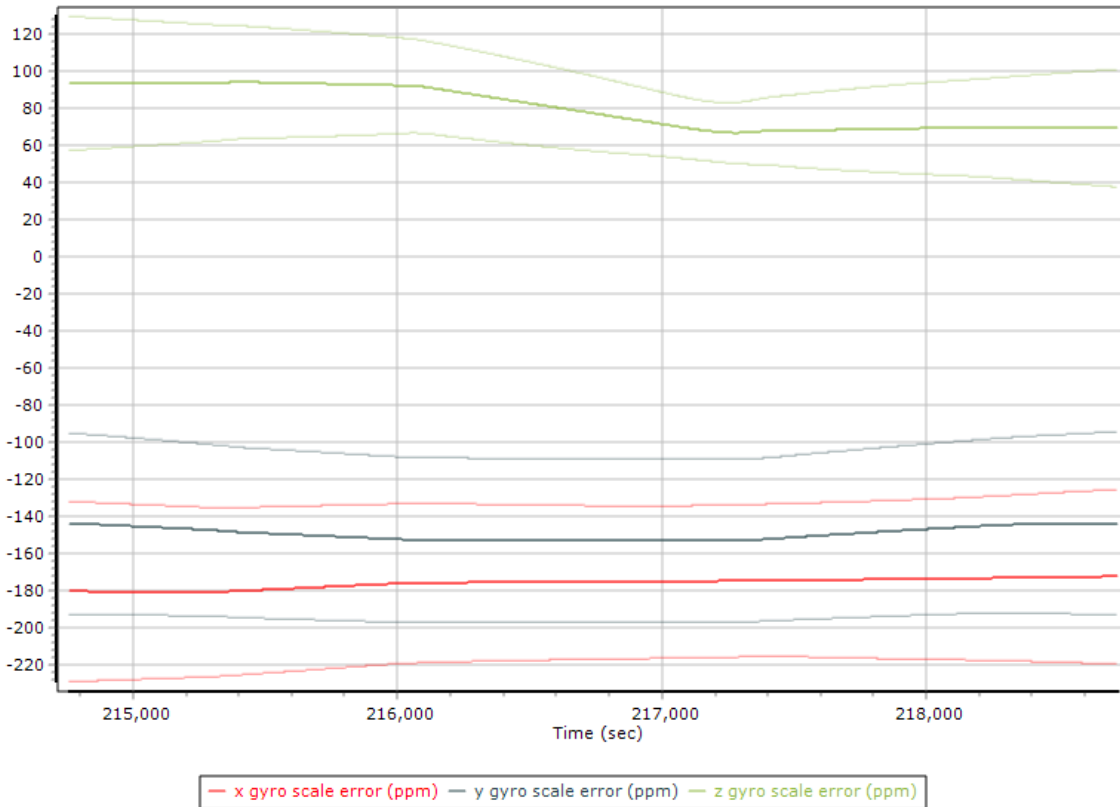
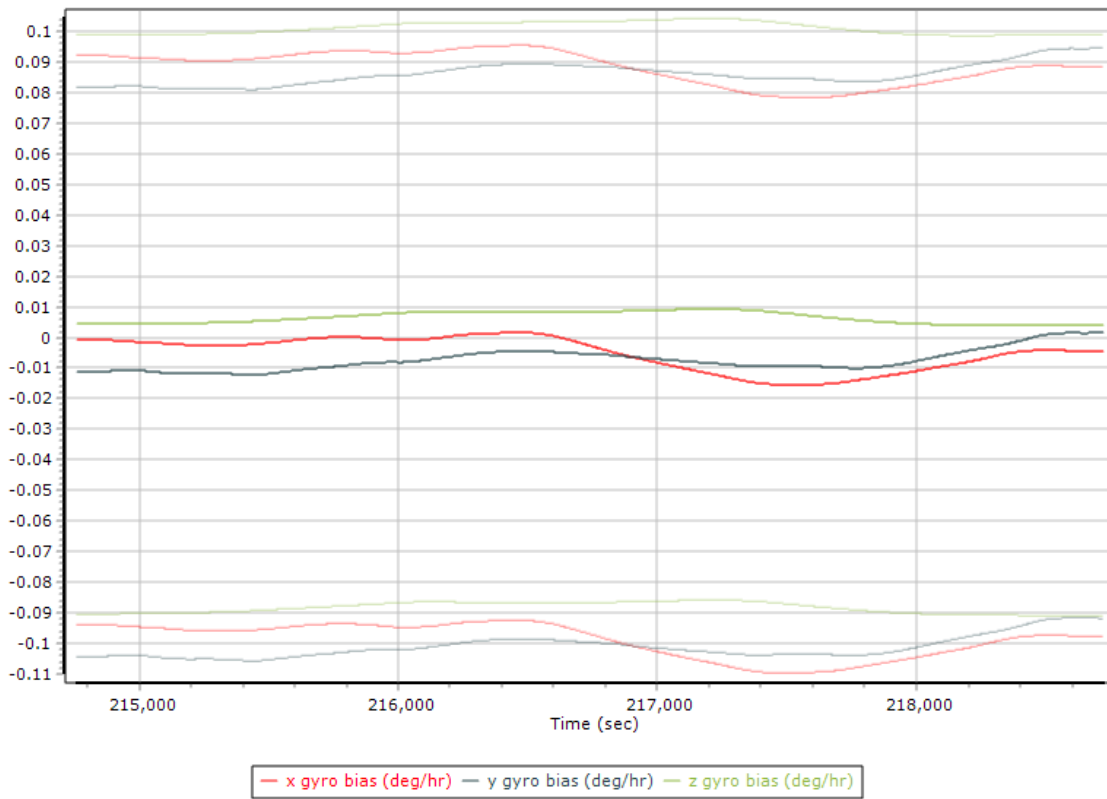
Sensor Error



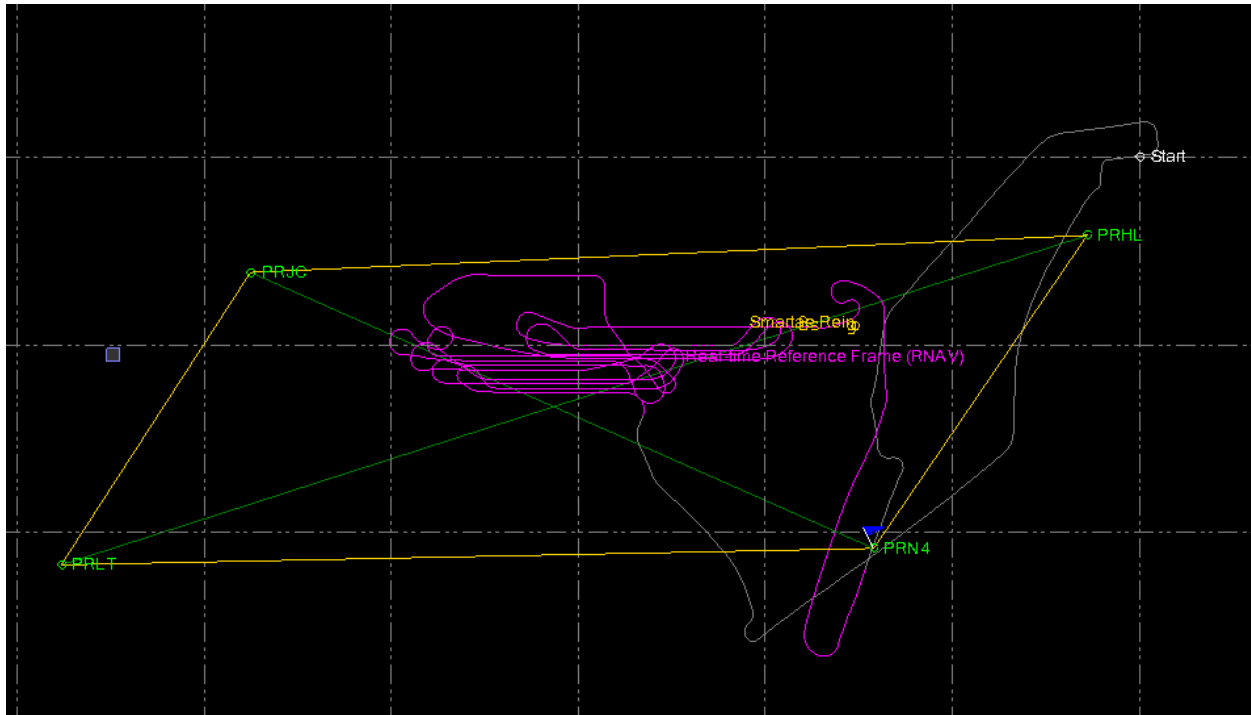
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



RBV18151A



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: -0.037 m	X: 0.000 deg
Y: 0.007 m	Y: 0.000 deg
Z: -0.985 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

End

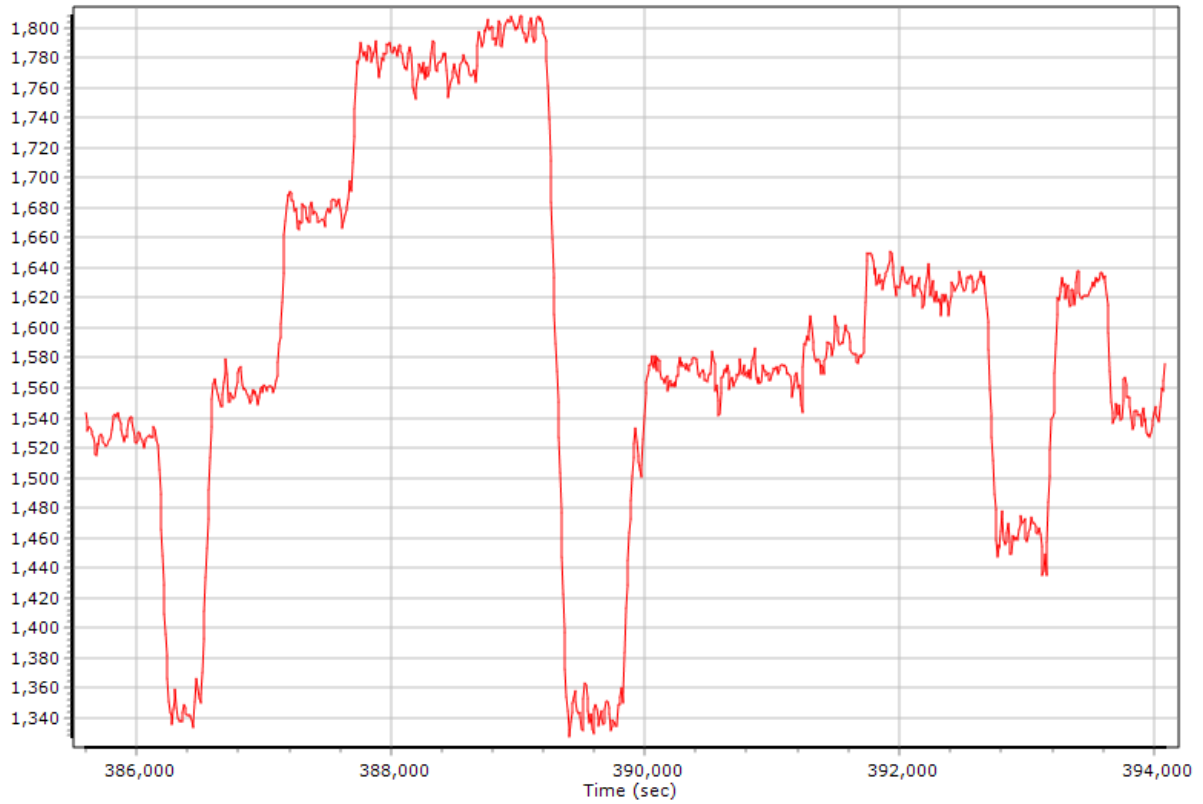
Entire time interval

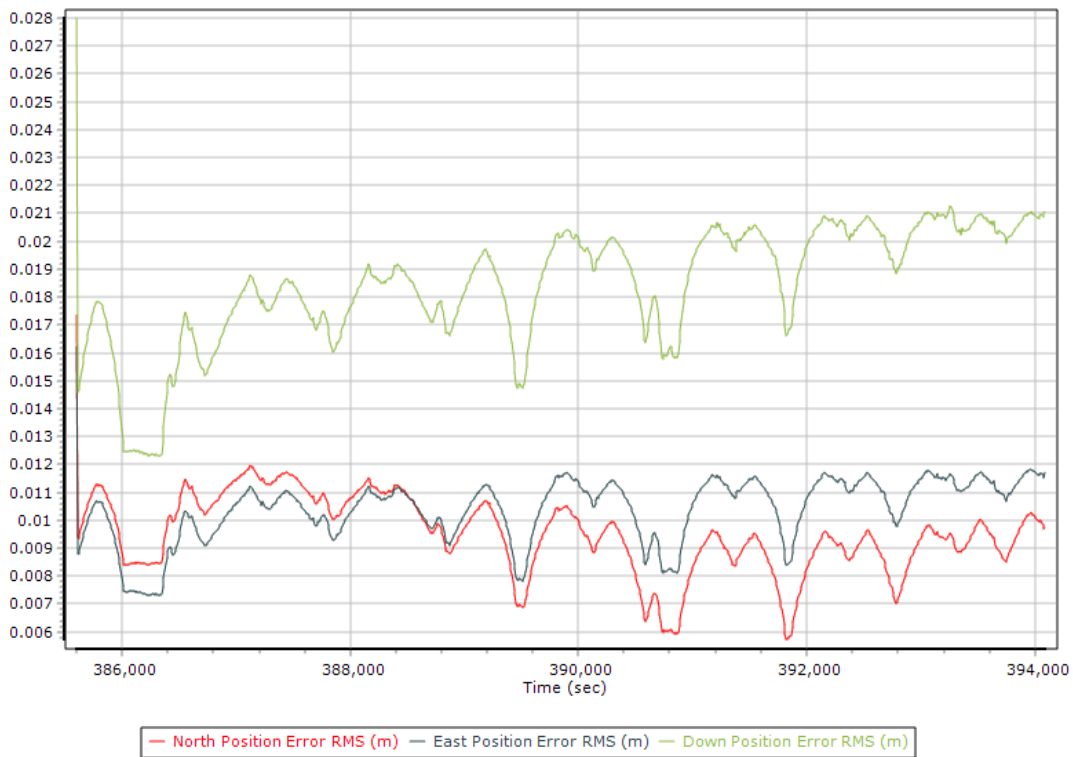
Seconds of start week

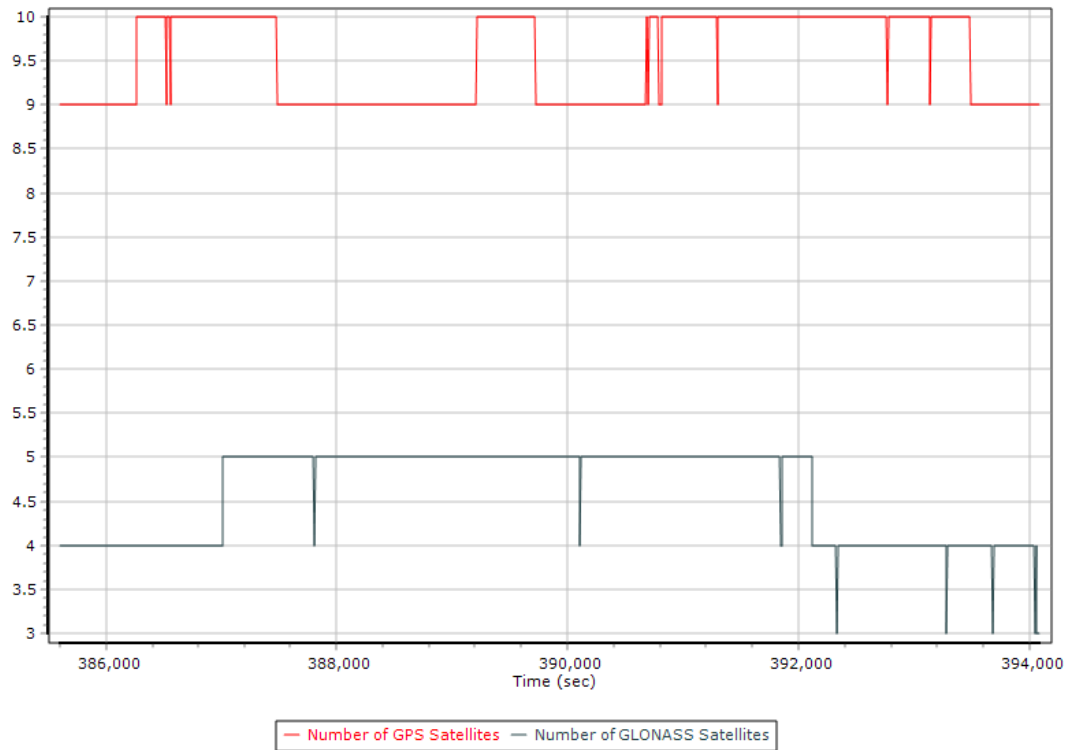
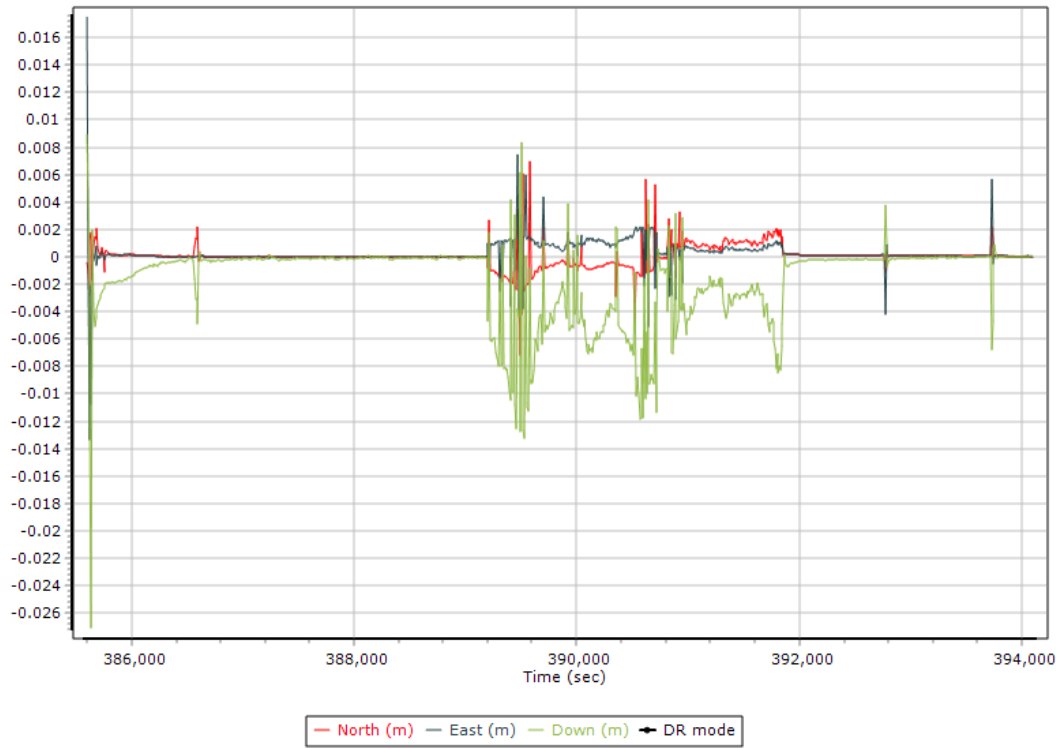
UTC Offset

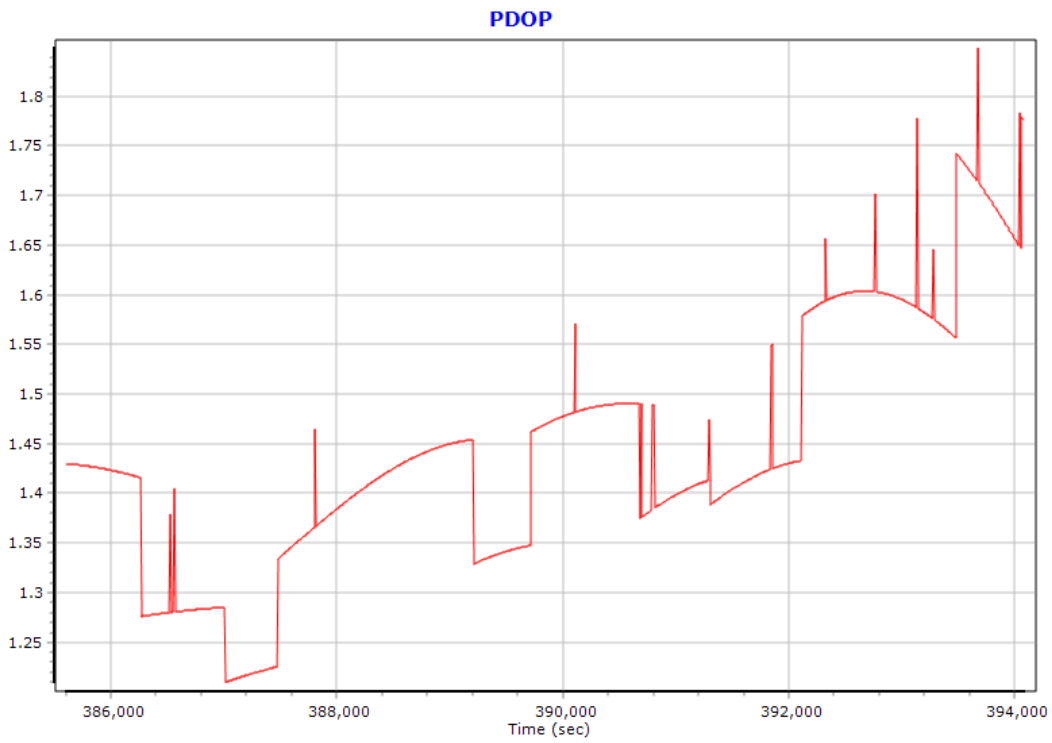
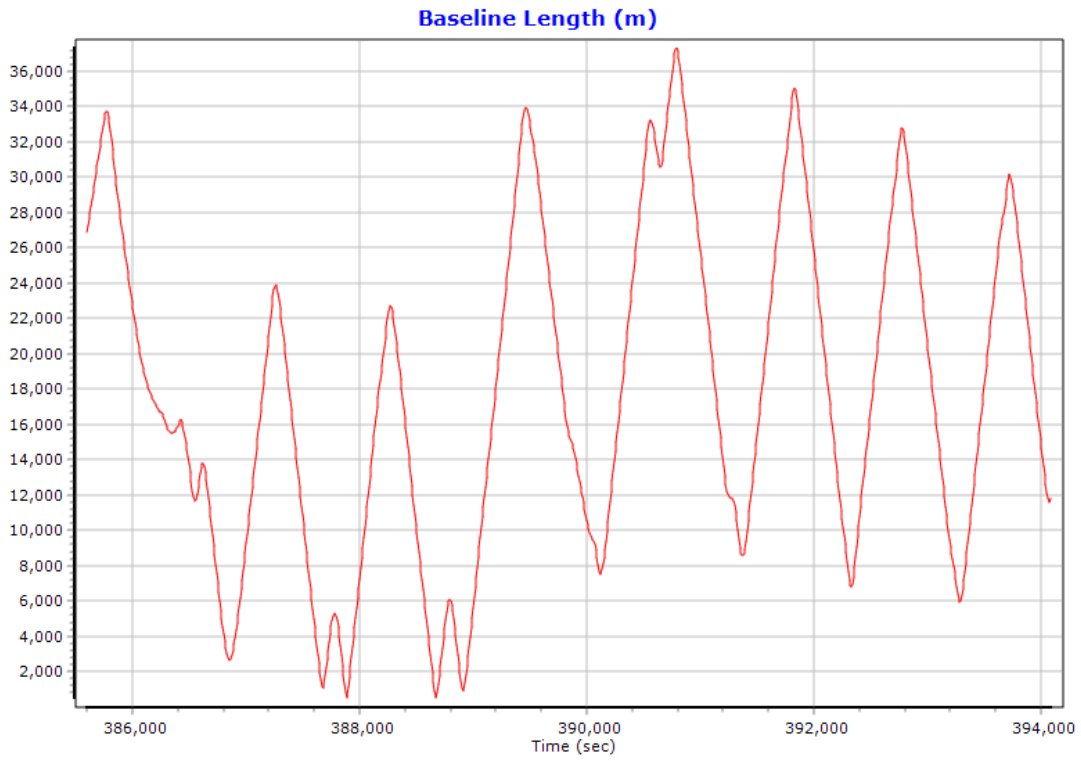
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

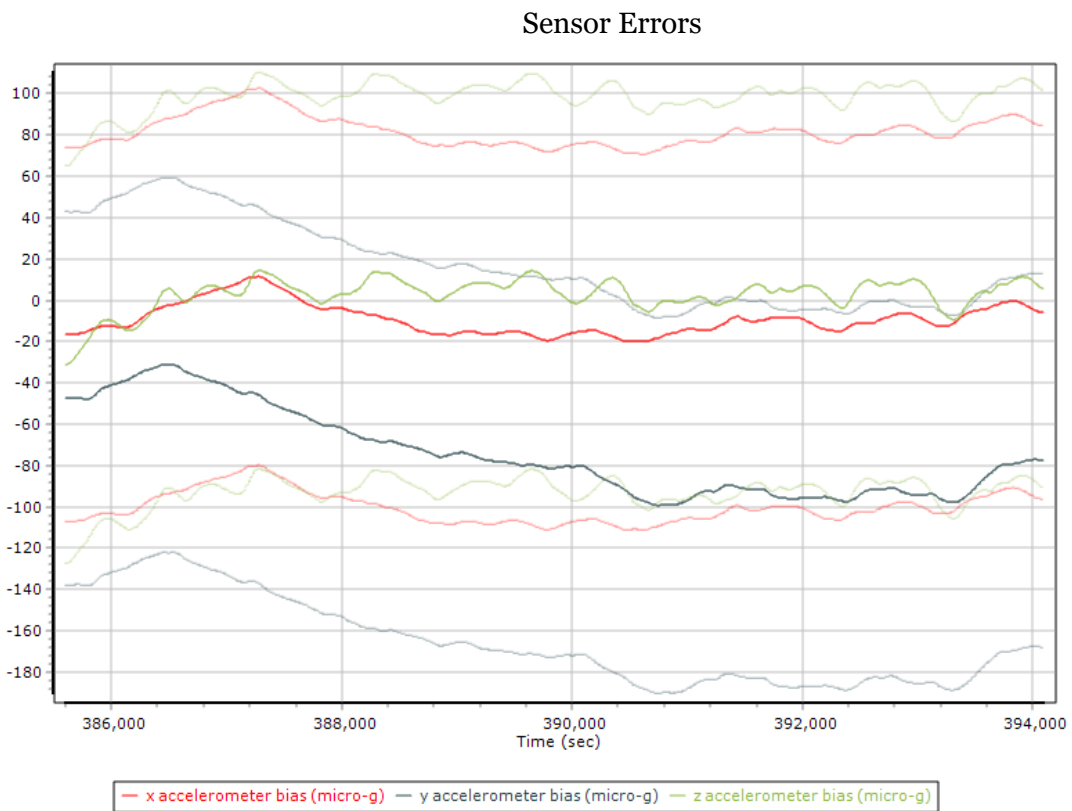
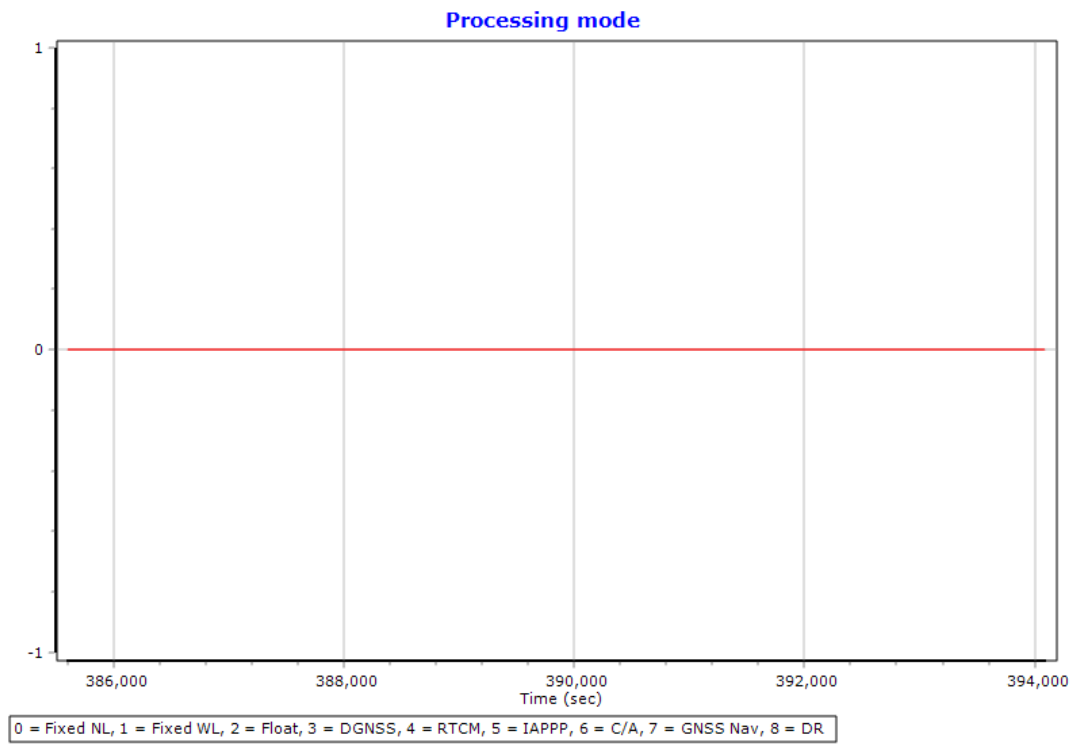
Altitude (m)

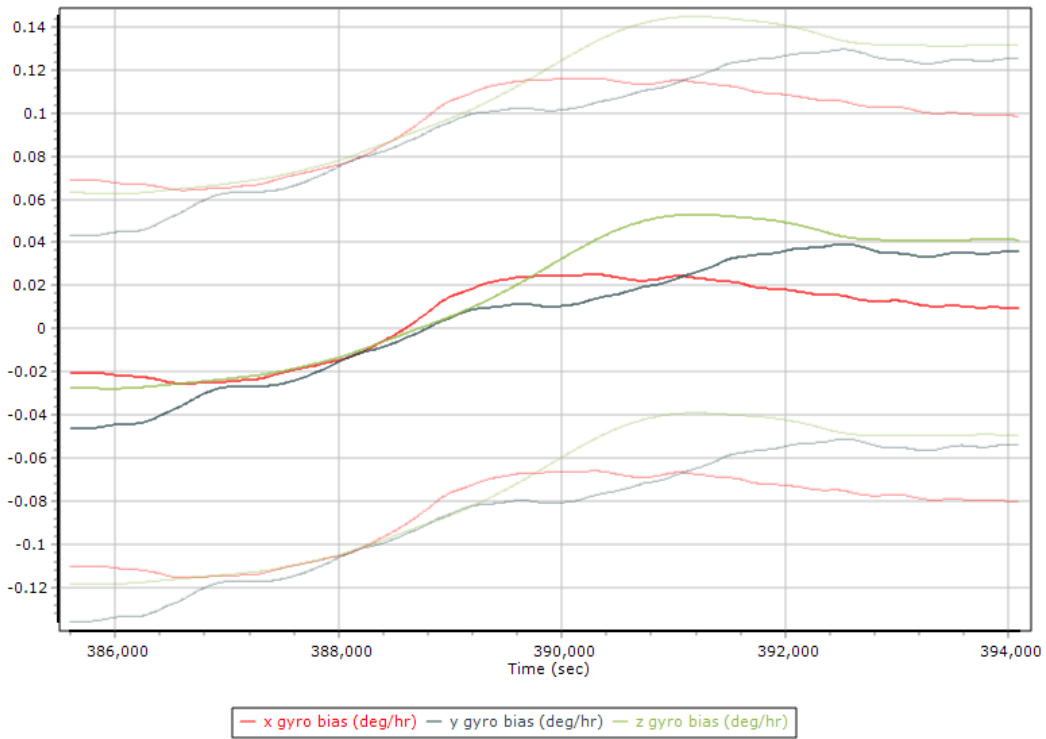
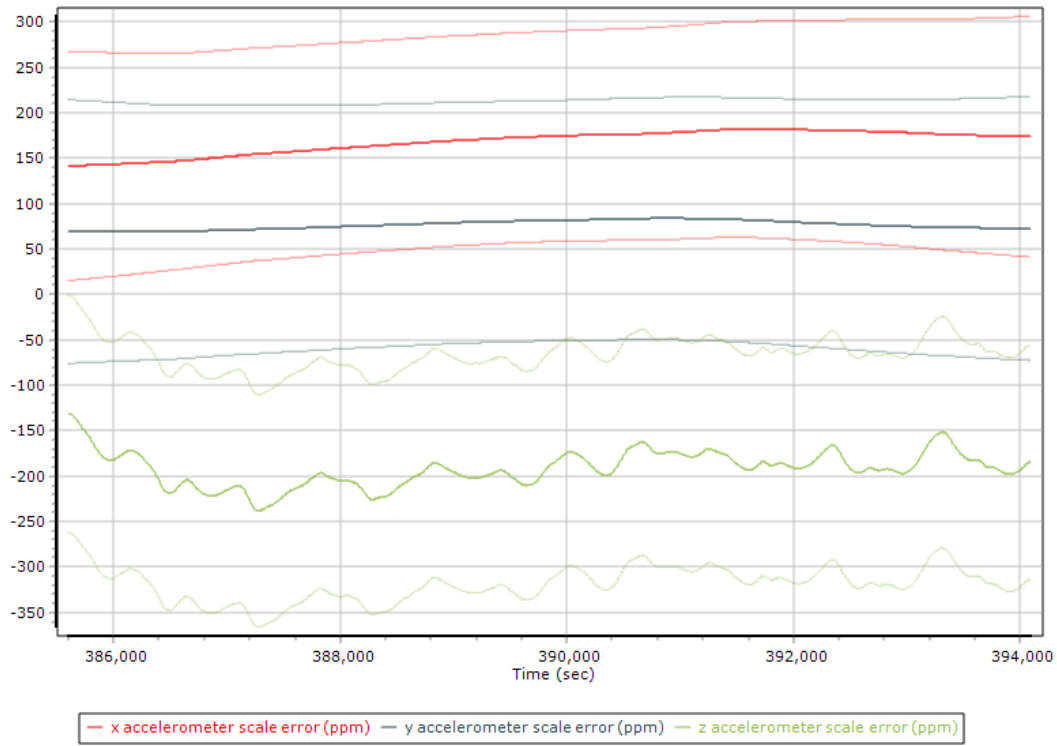


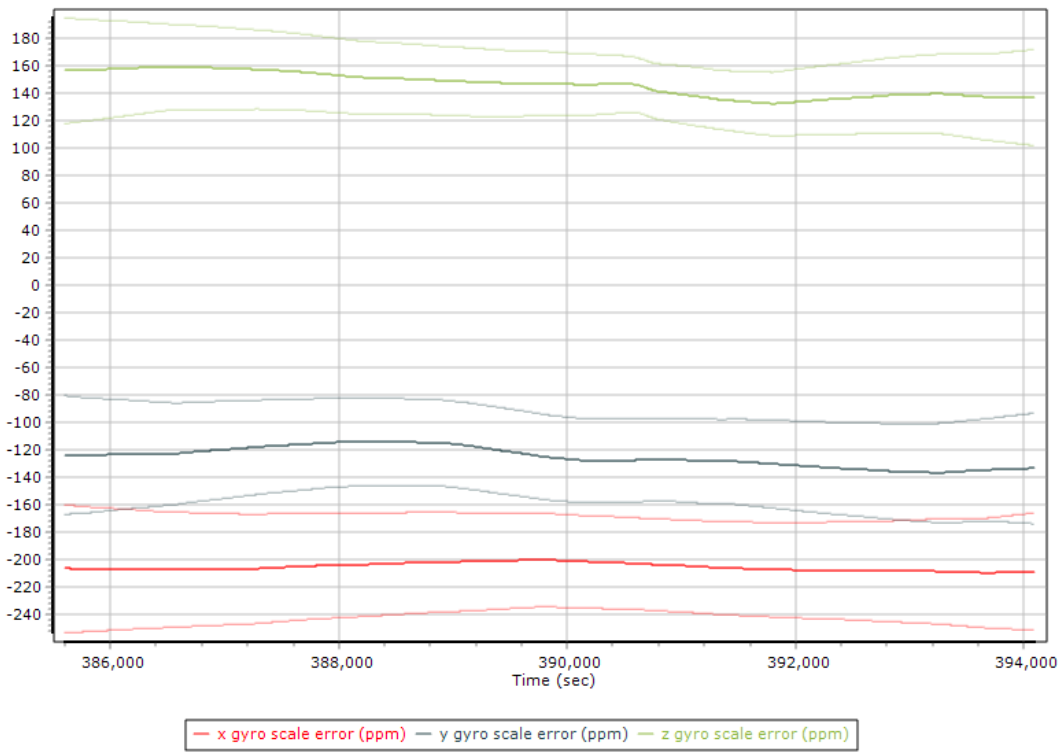




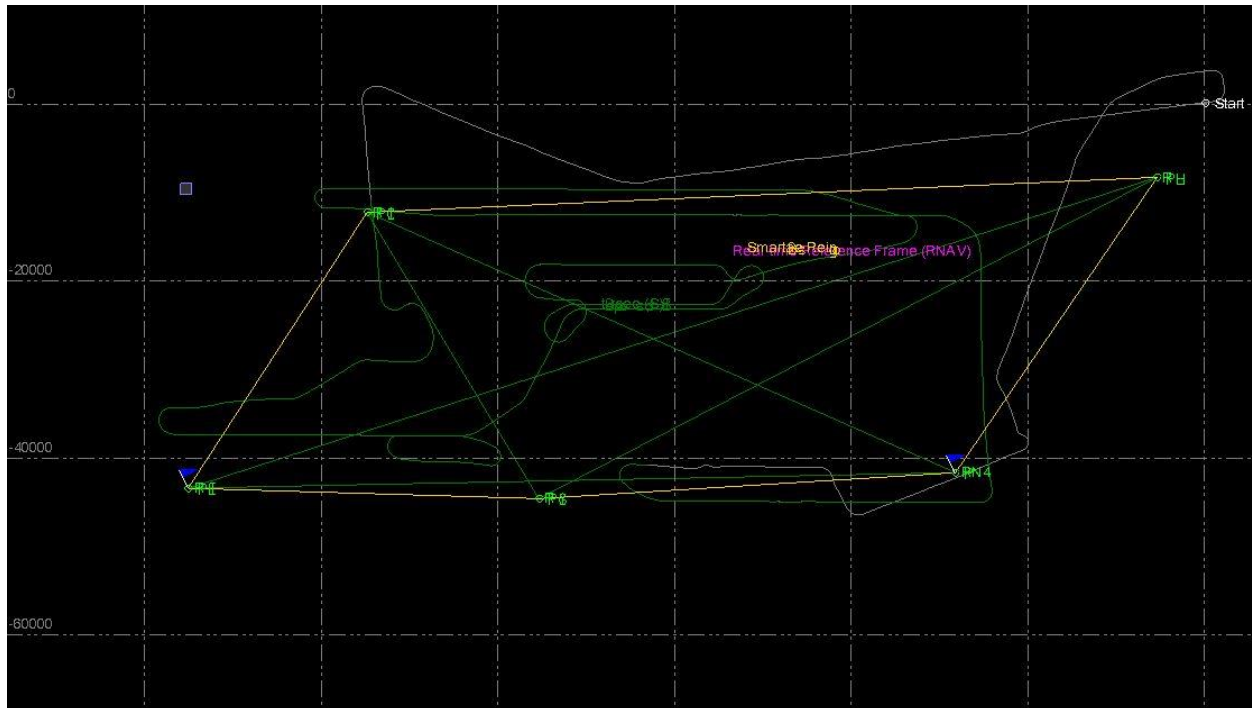


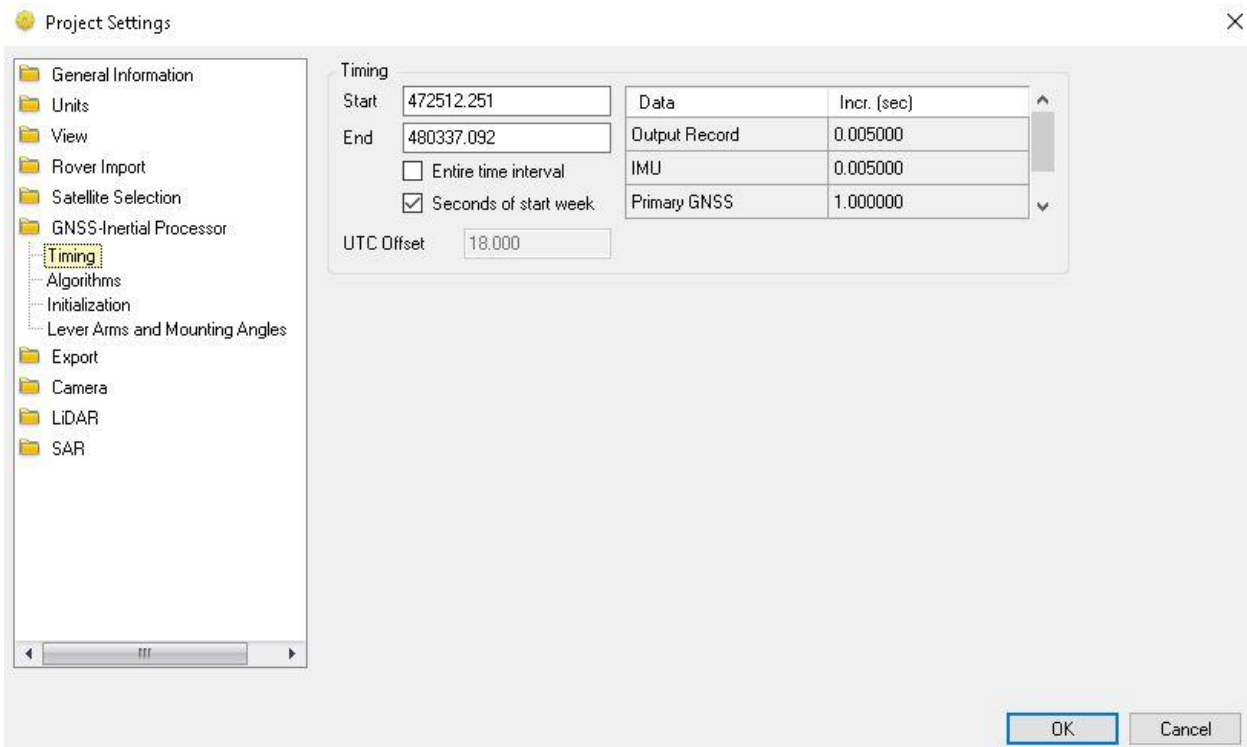
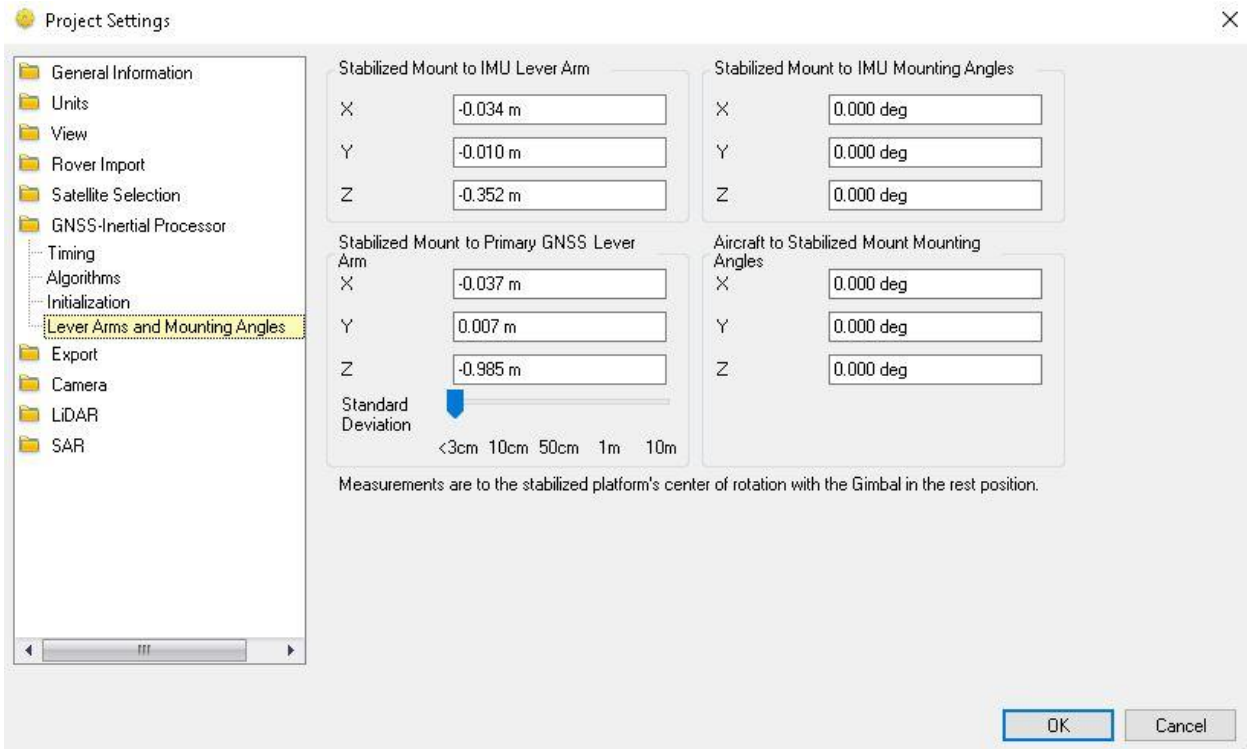


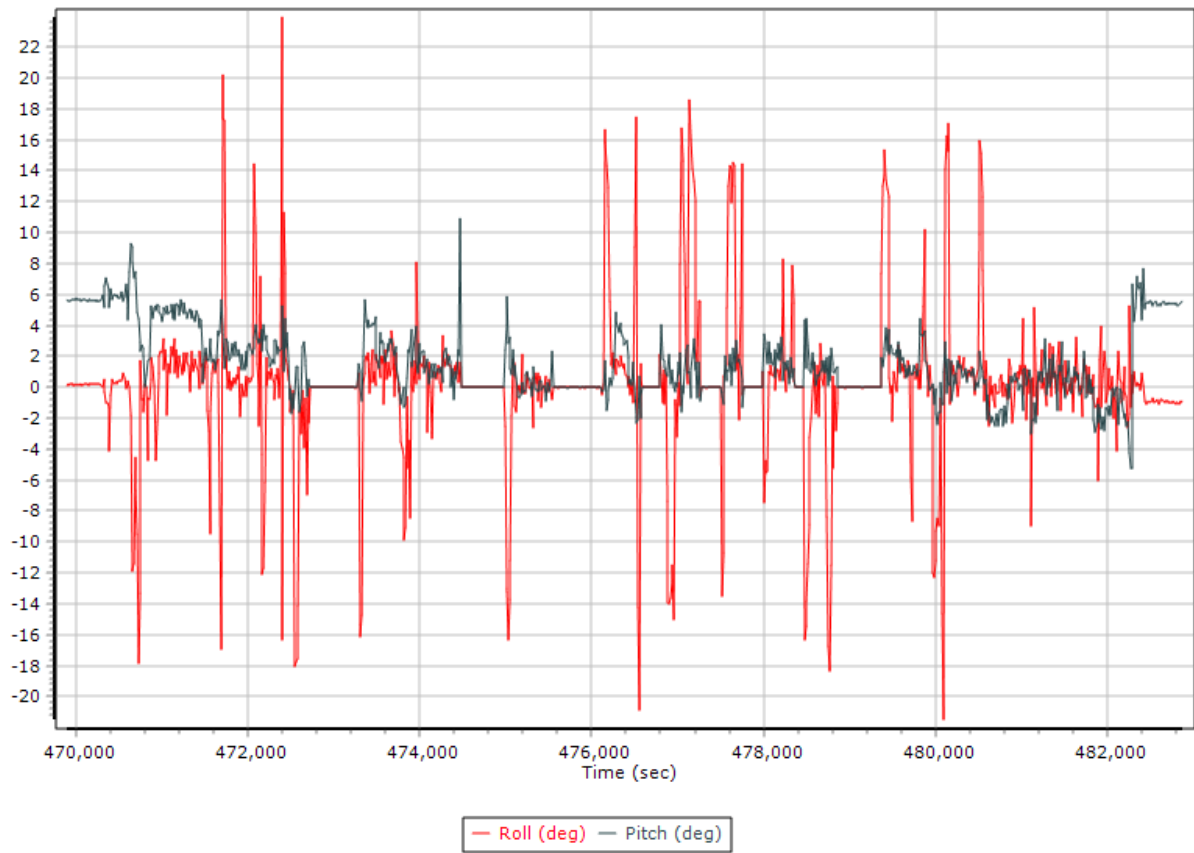
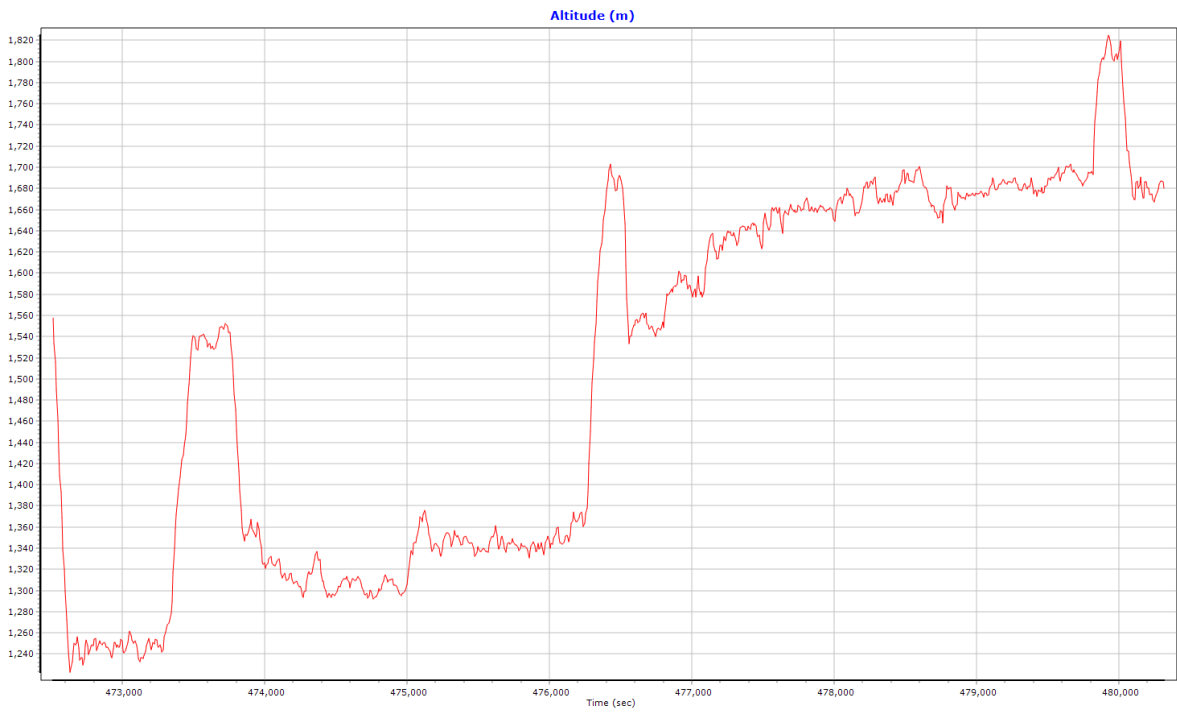


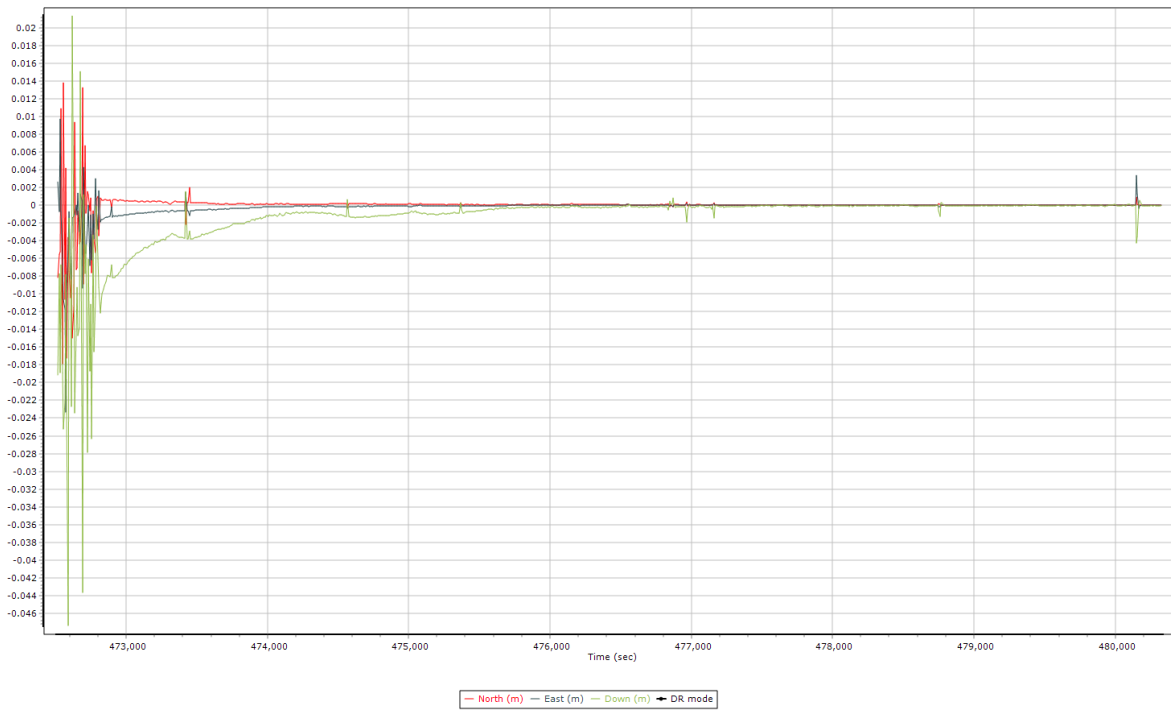
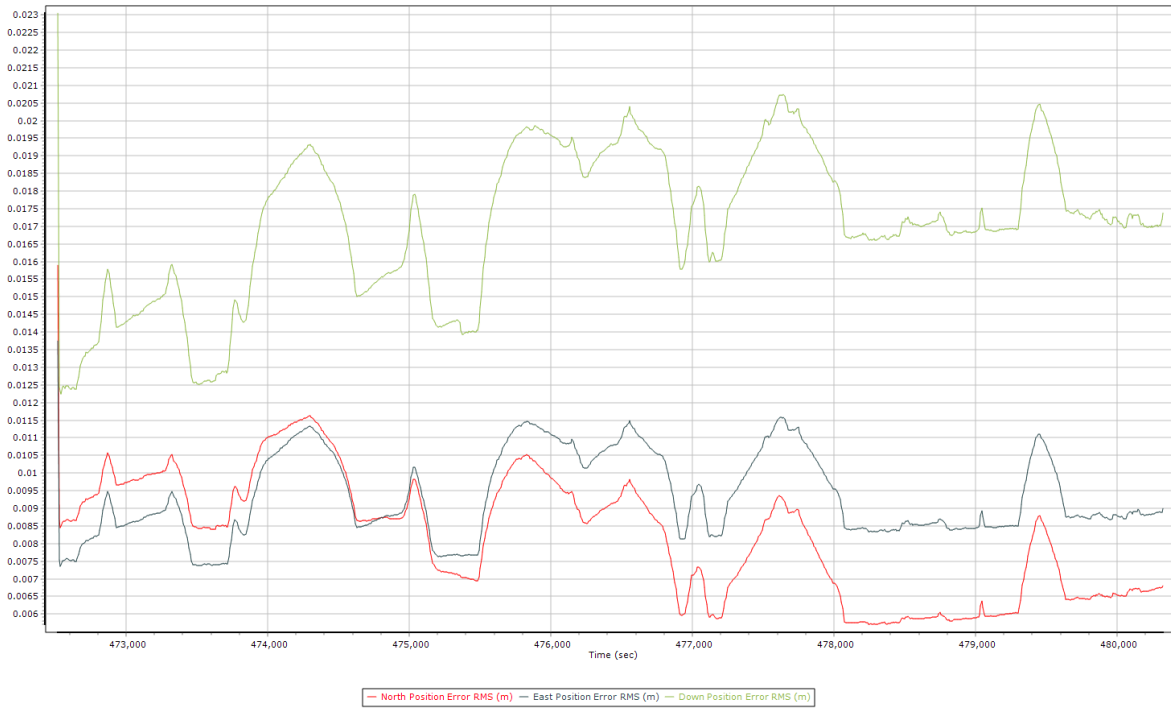


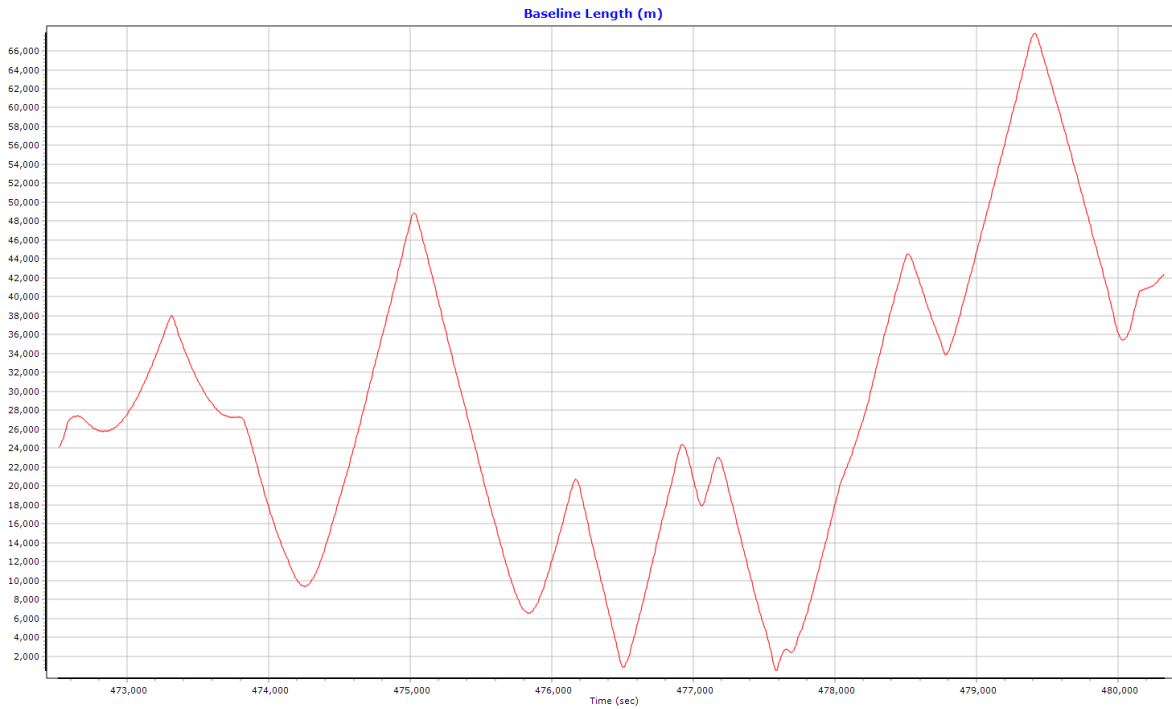
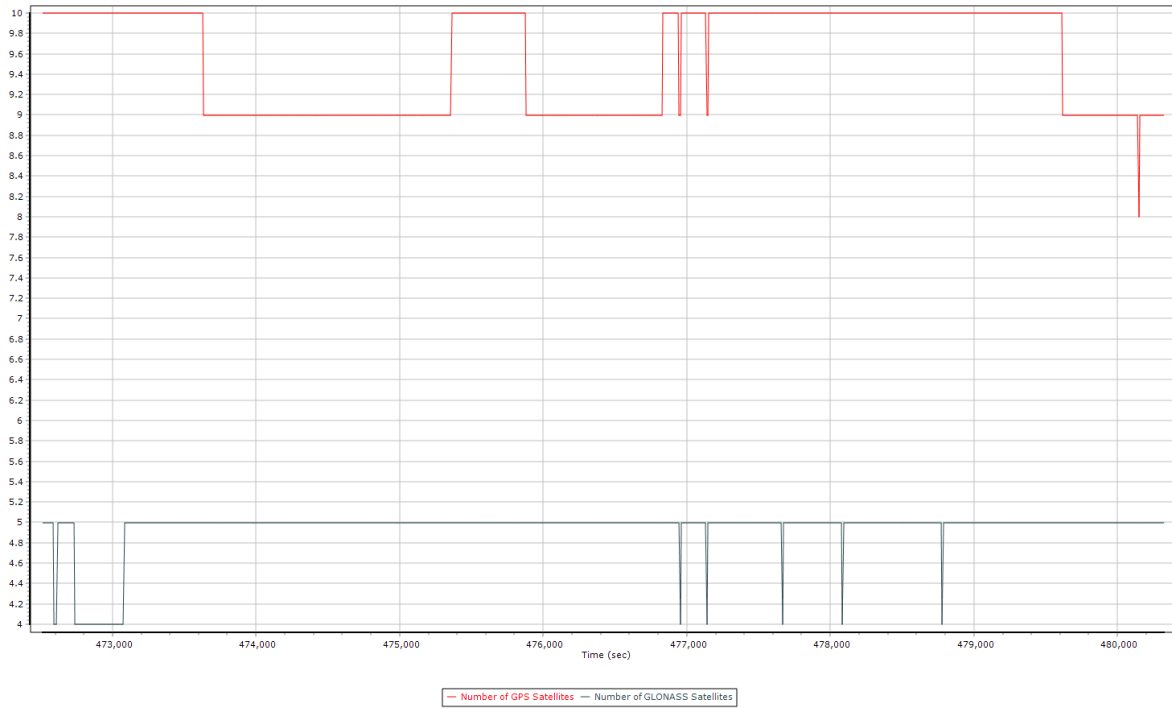
RBV18152A

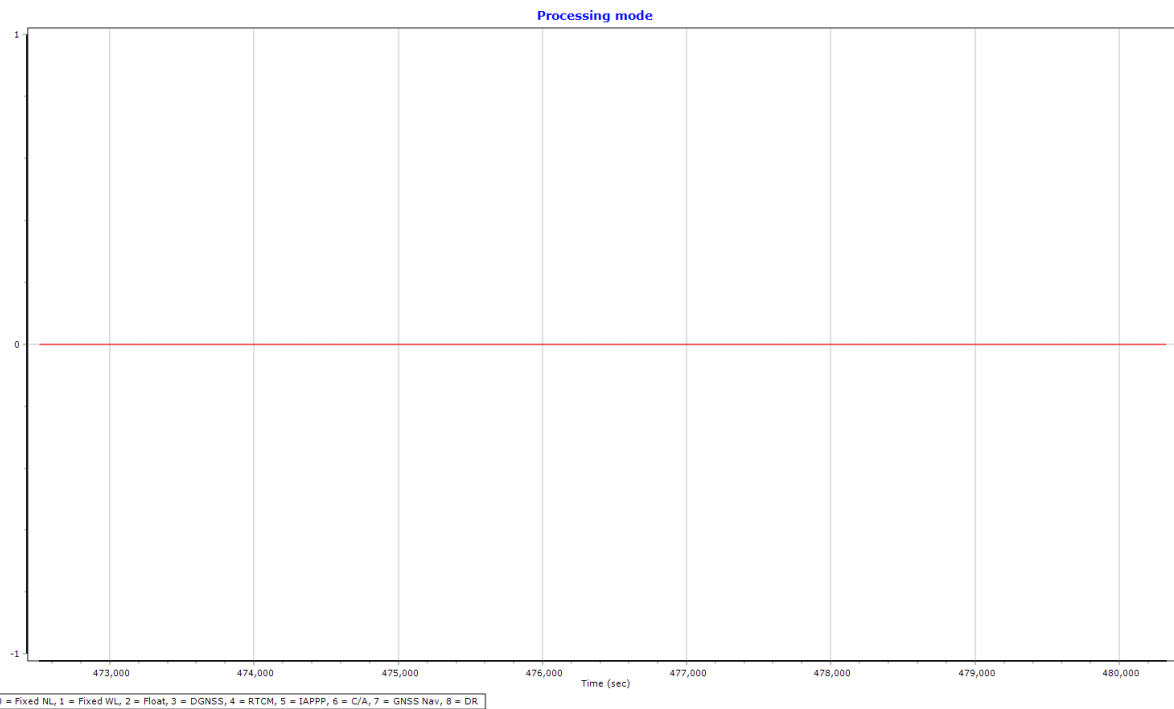
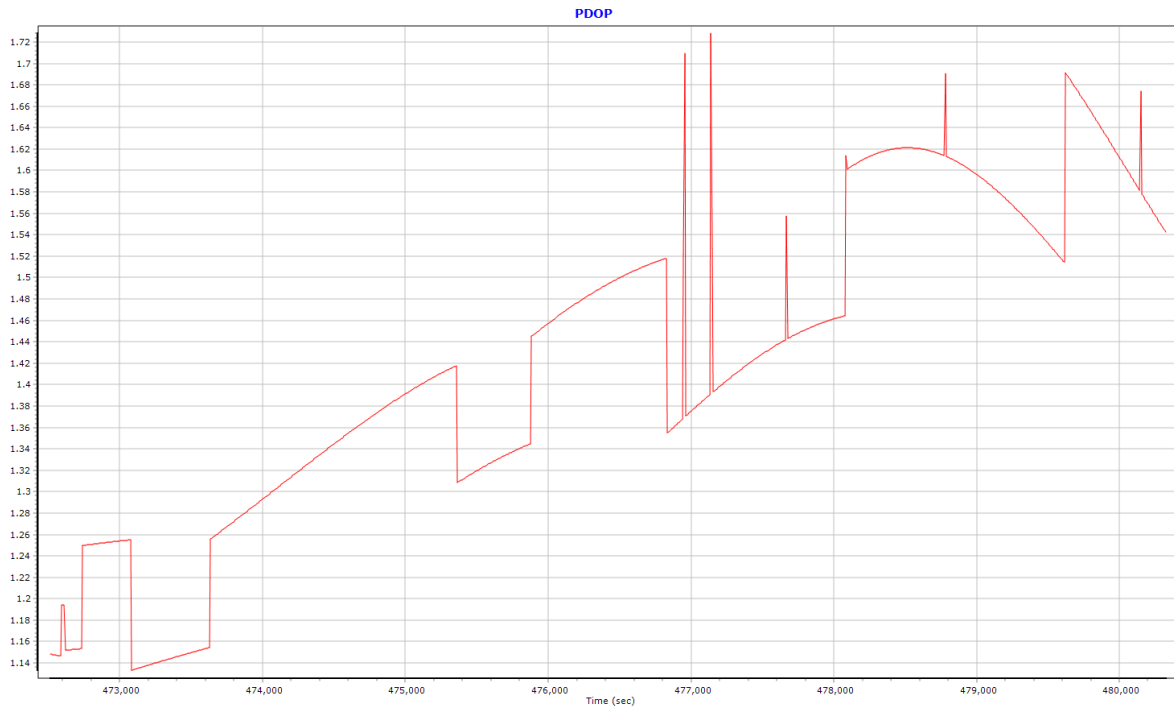




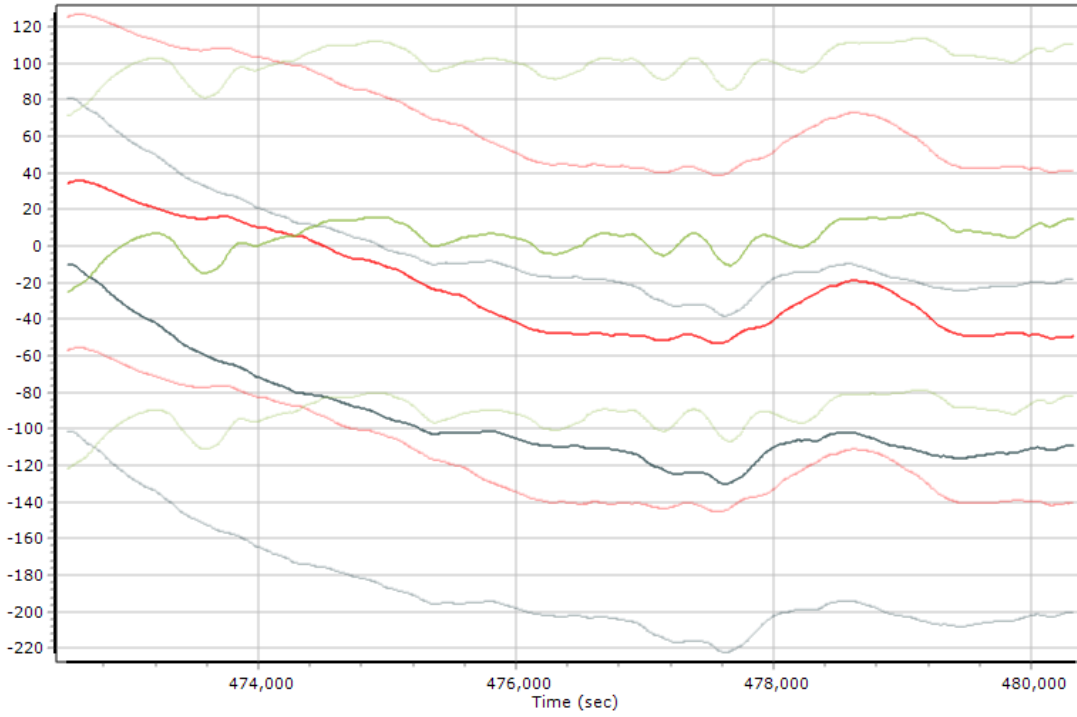




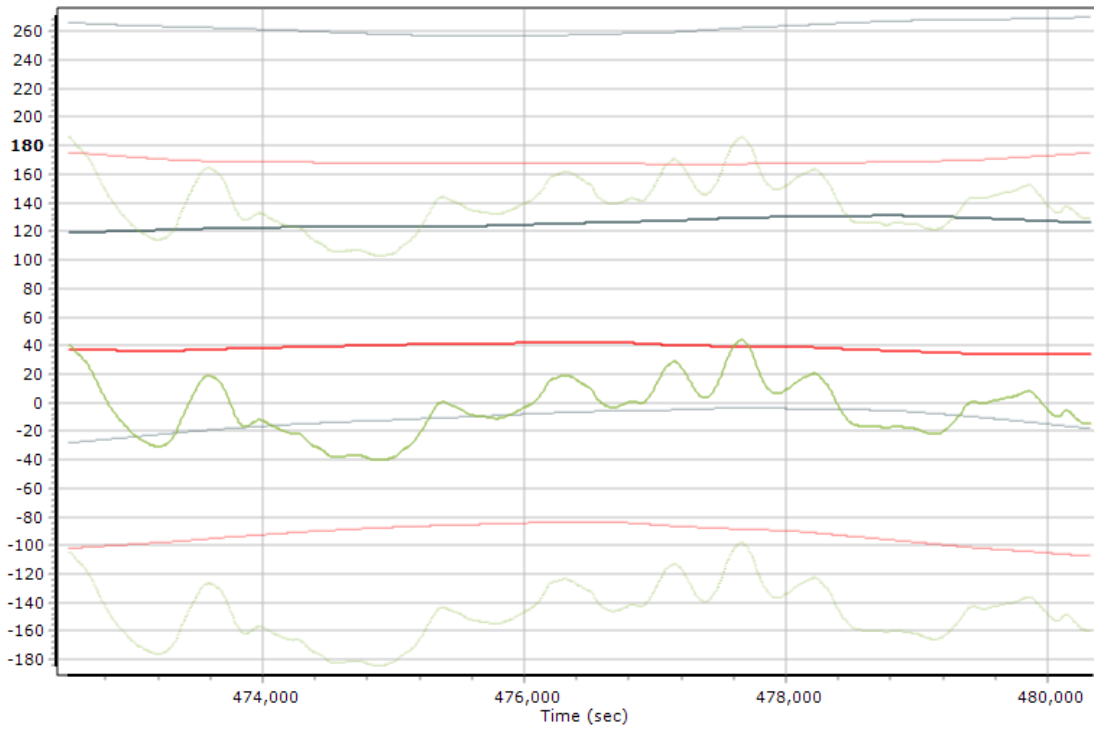




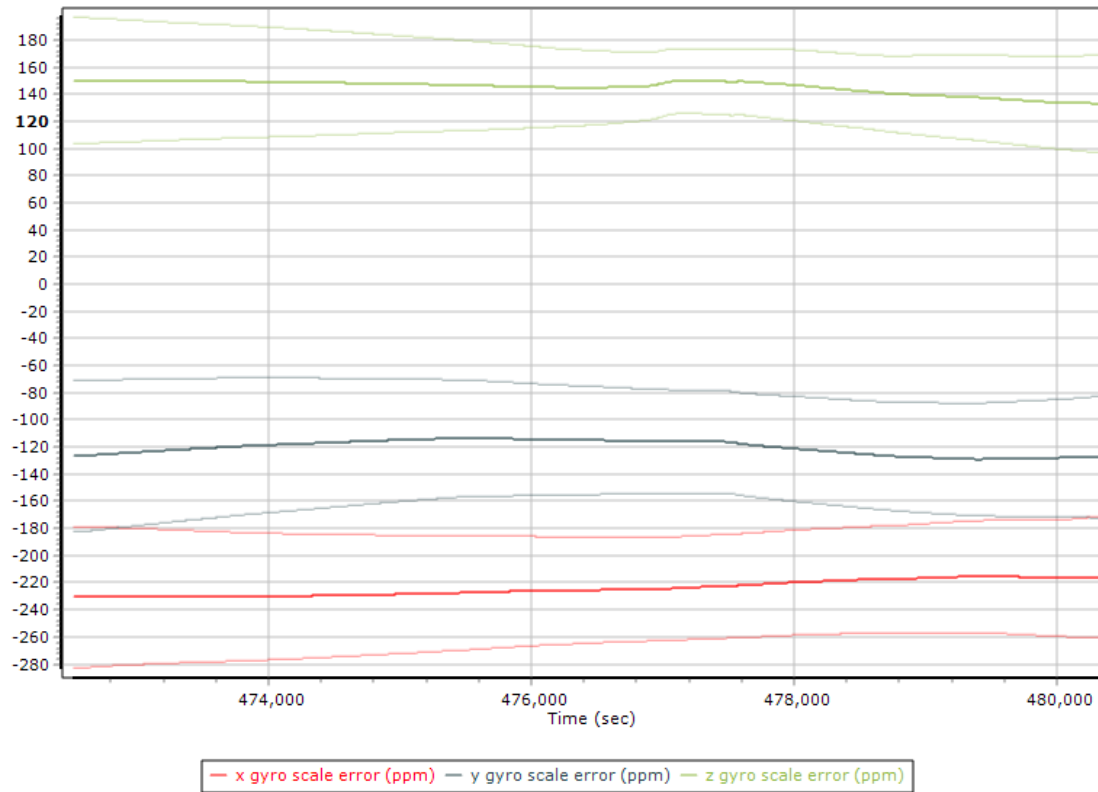
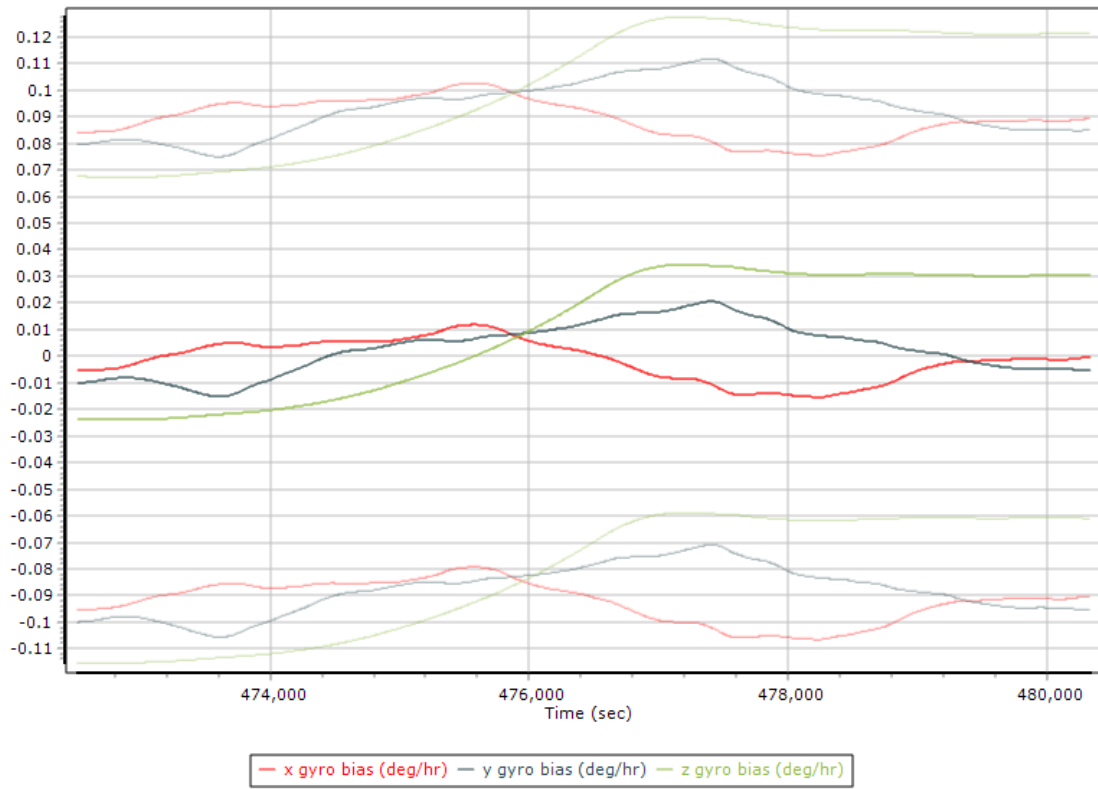
Sensor Errors



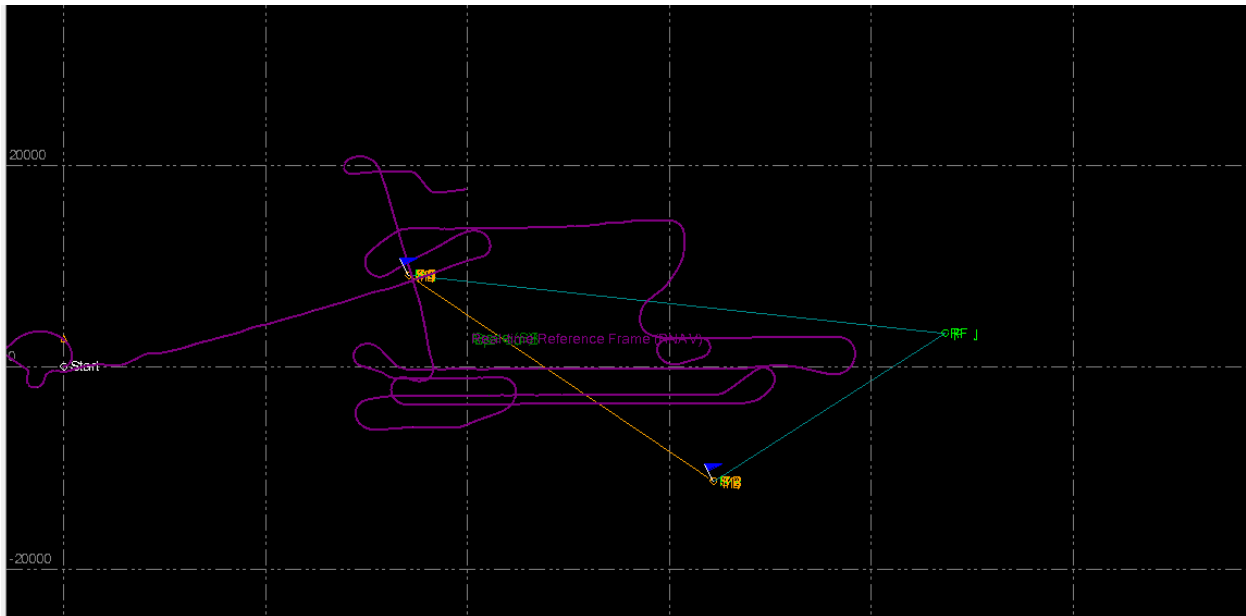
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



RBV18155A



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

Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.037 m	0.007 m	-0.985 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

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

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

[OK] [Cancel]

Timing

Start

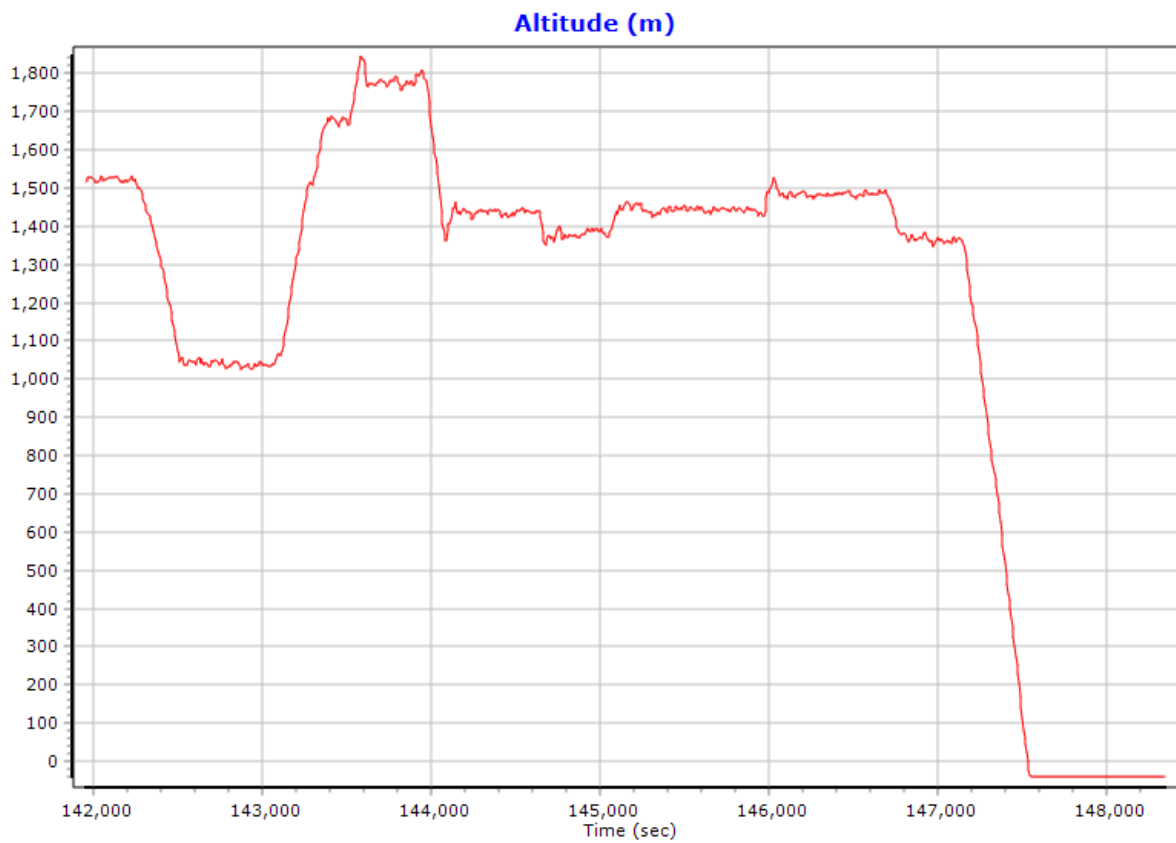
End

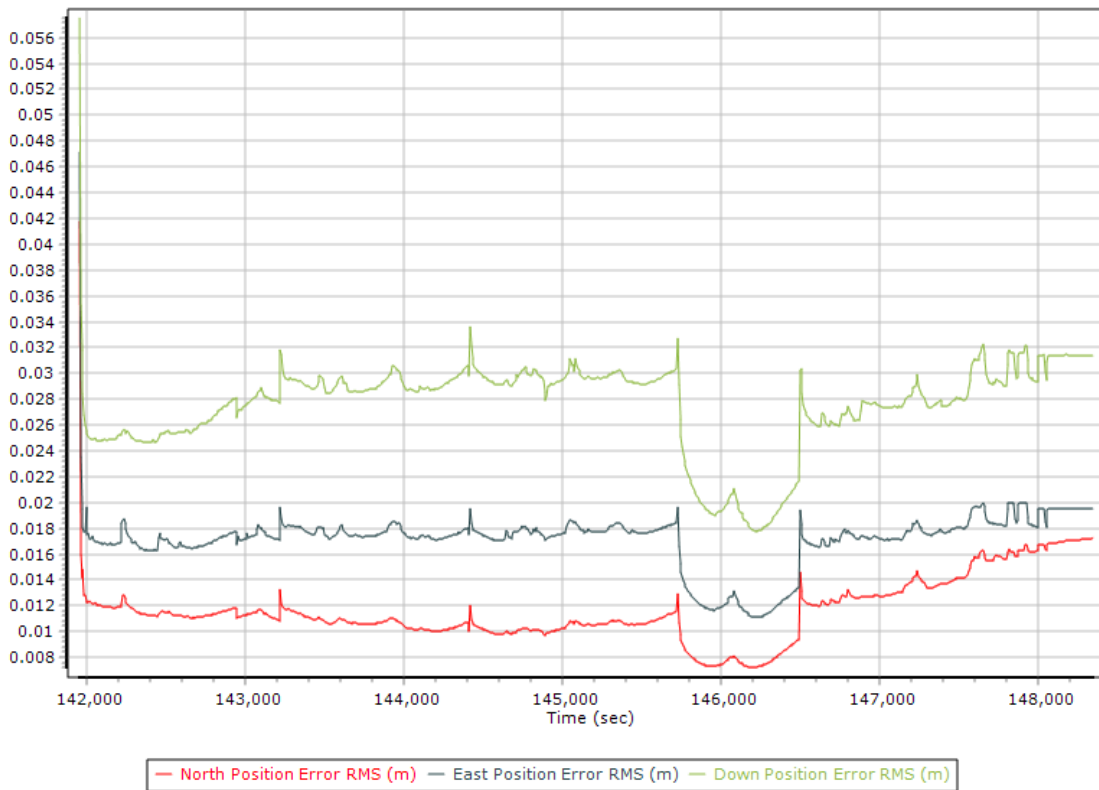
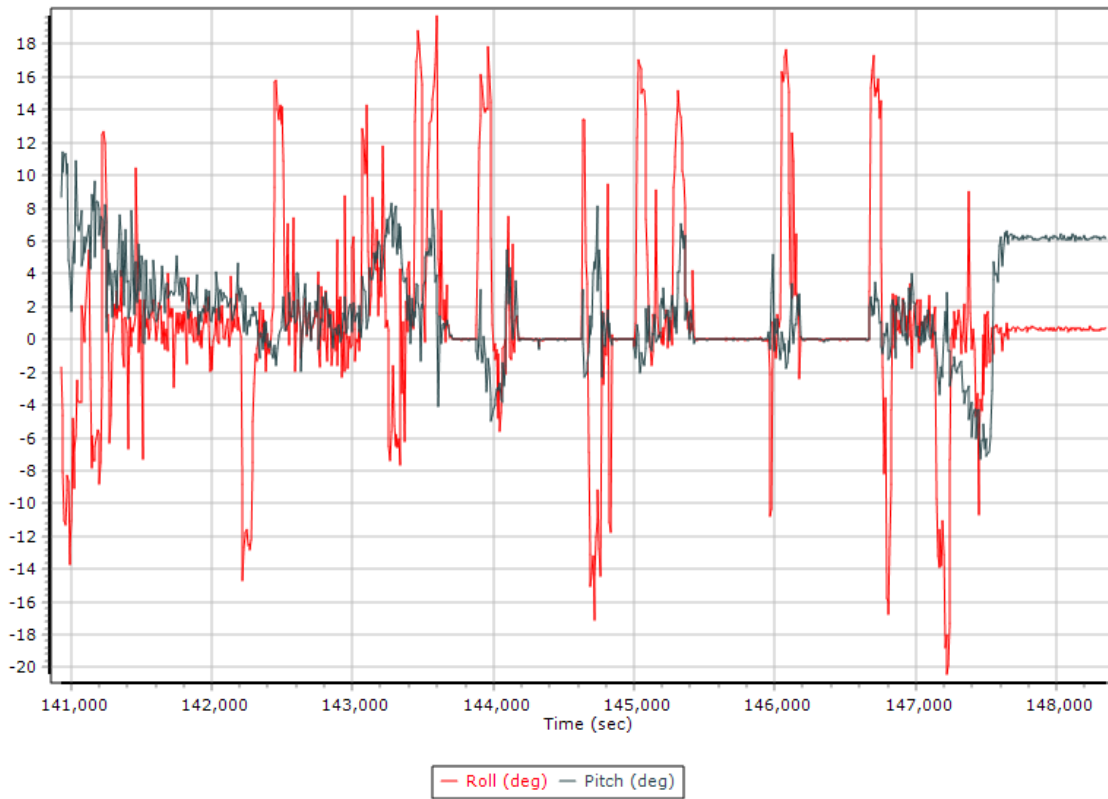
Entire time interval

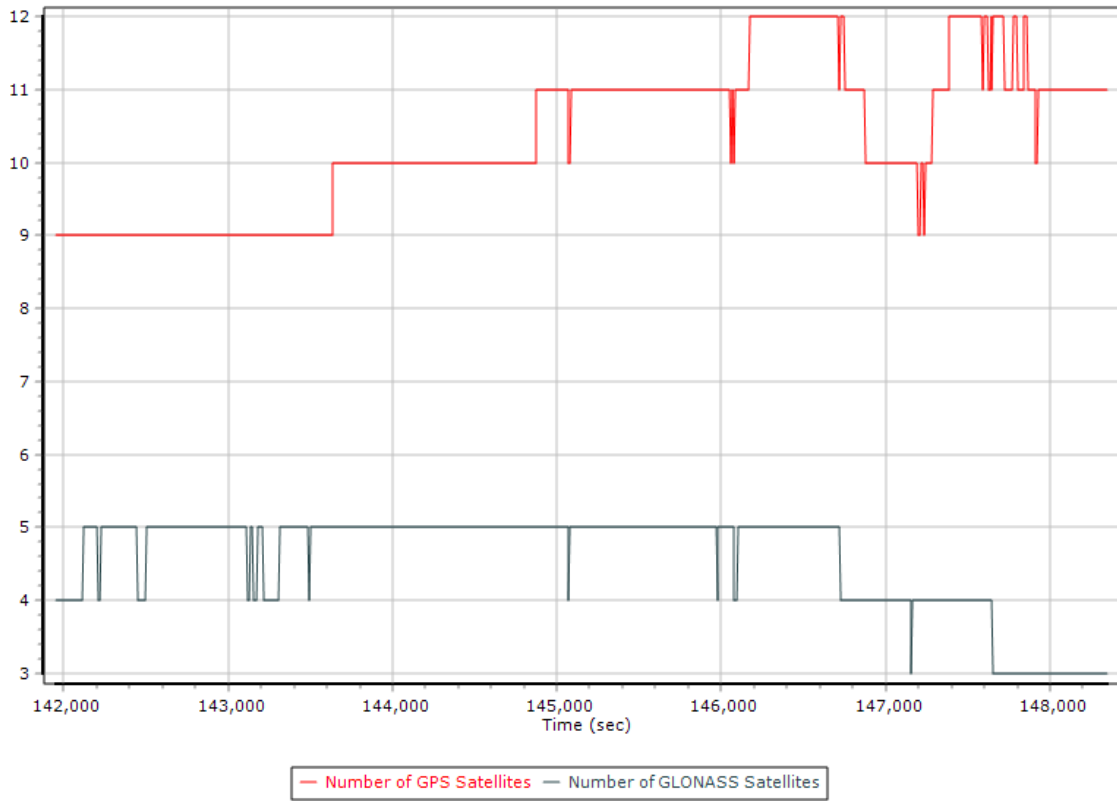
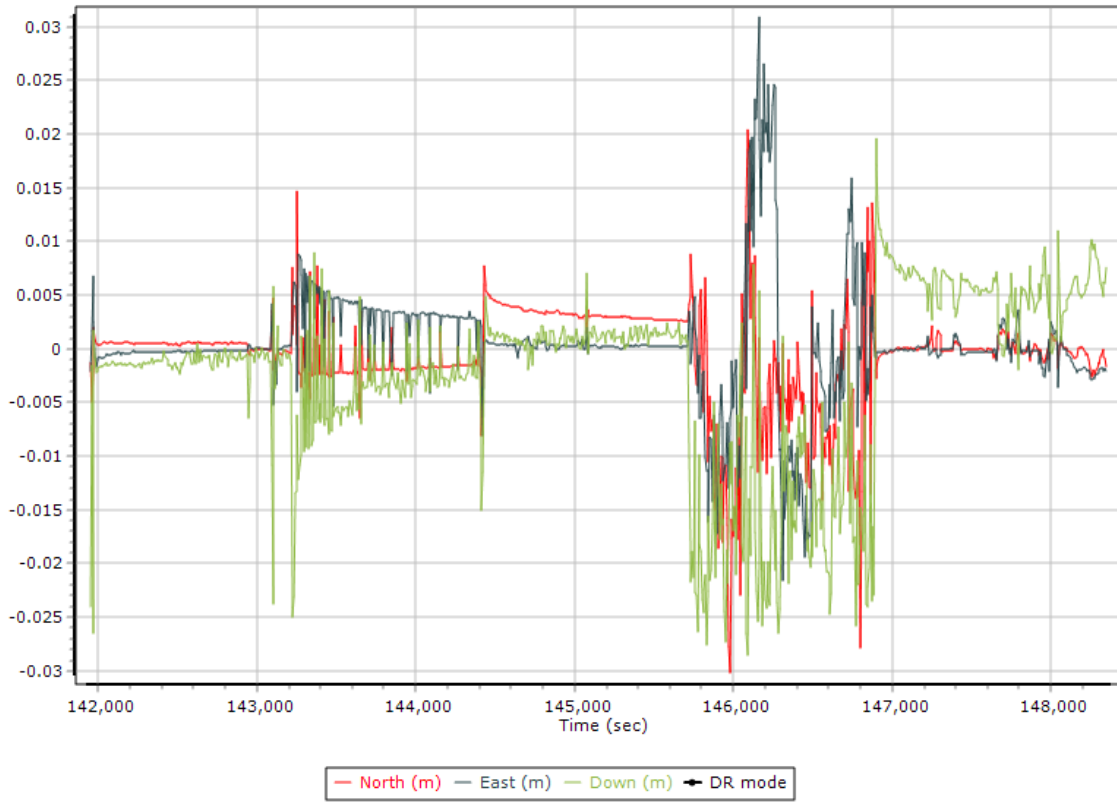
Seconds of start week

UTC Offset

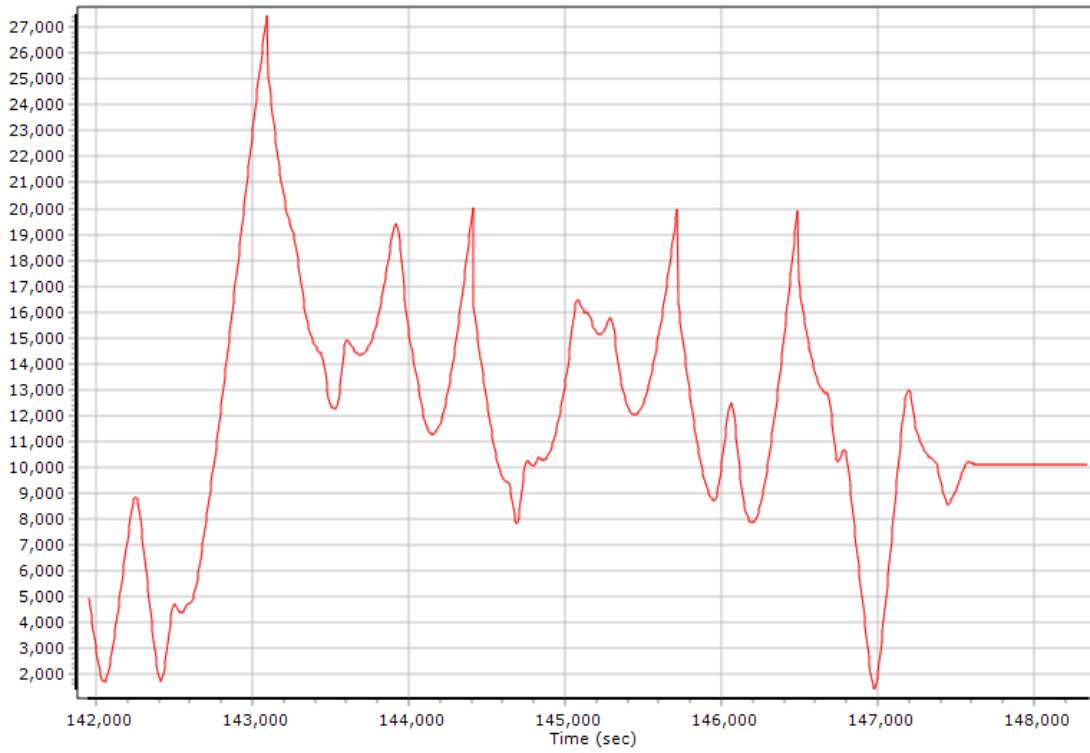
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



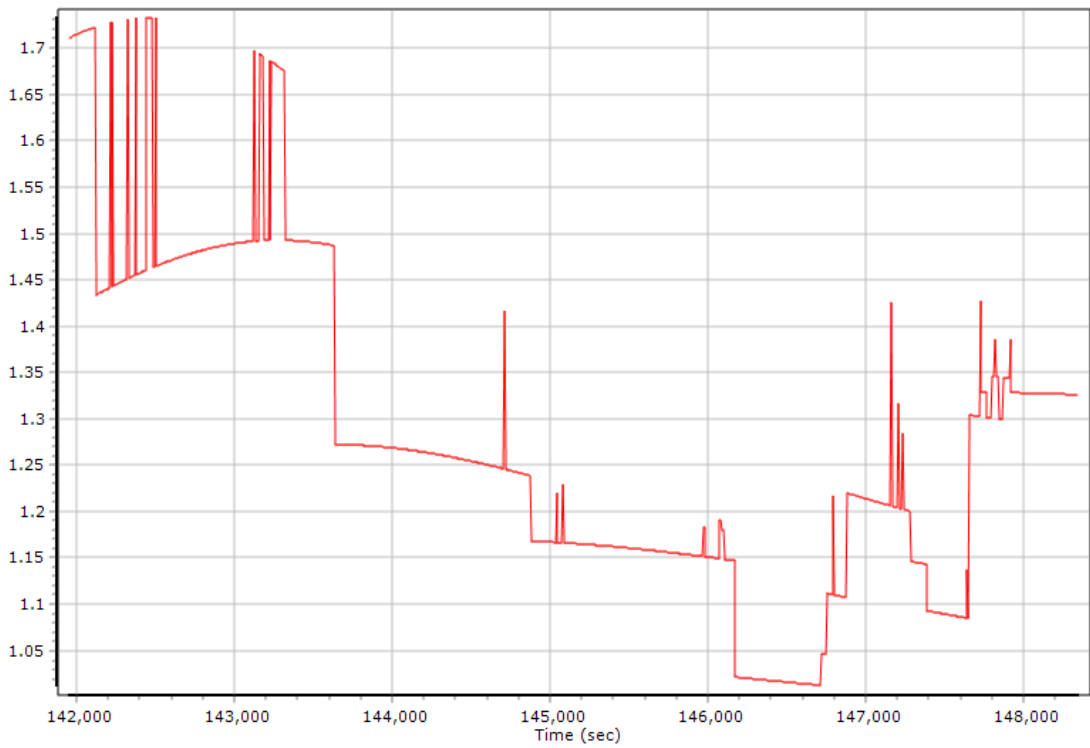


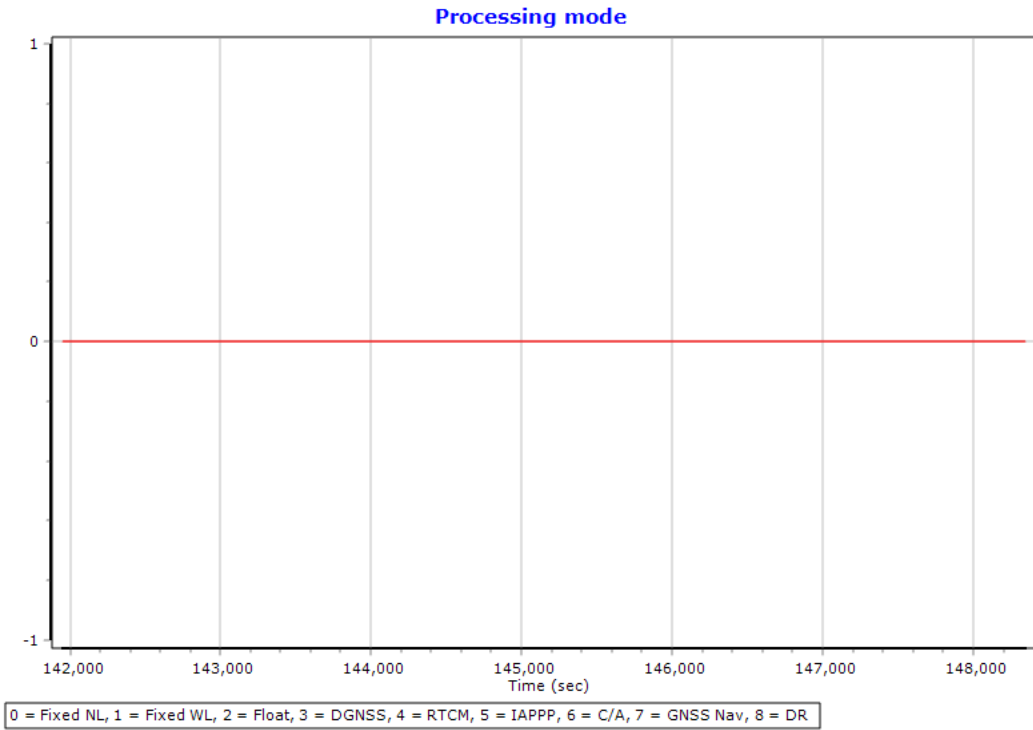


Baseline Length (m)

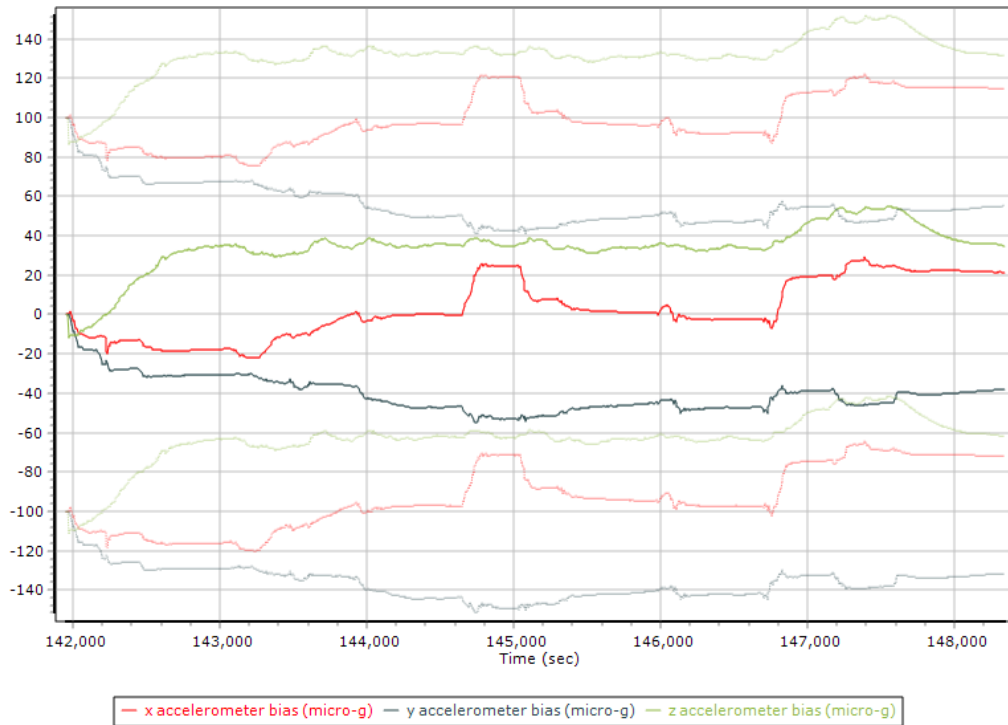


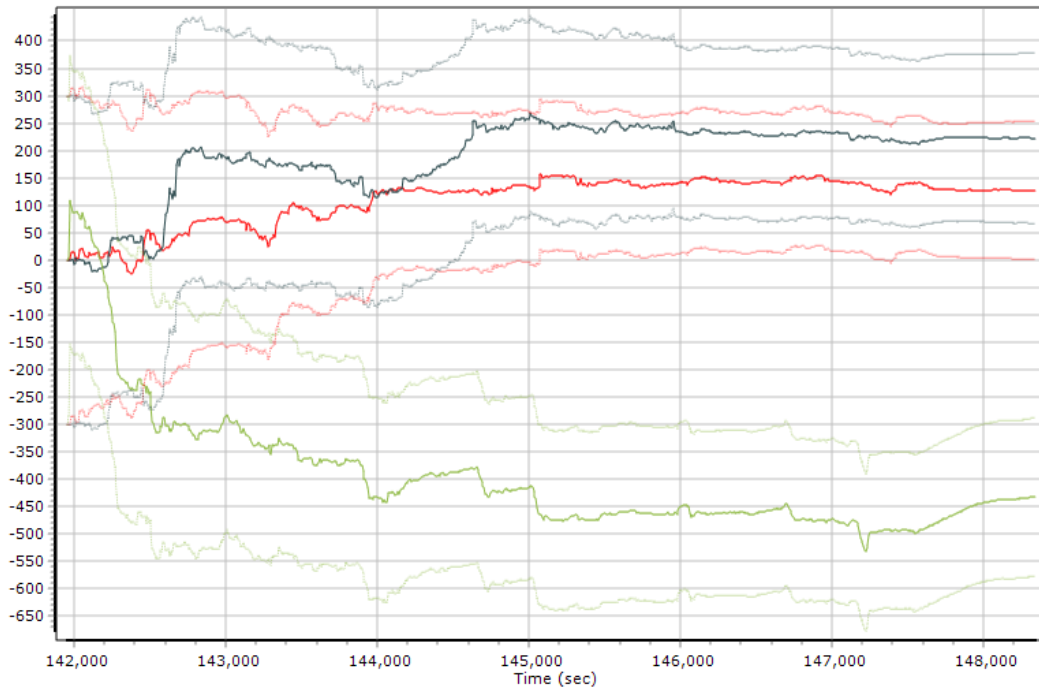
PDOP



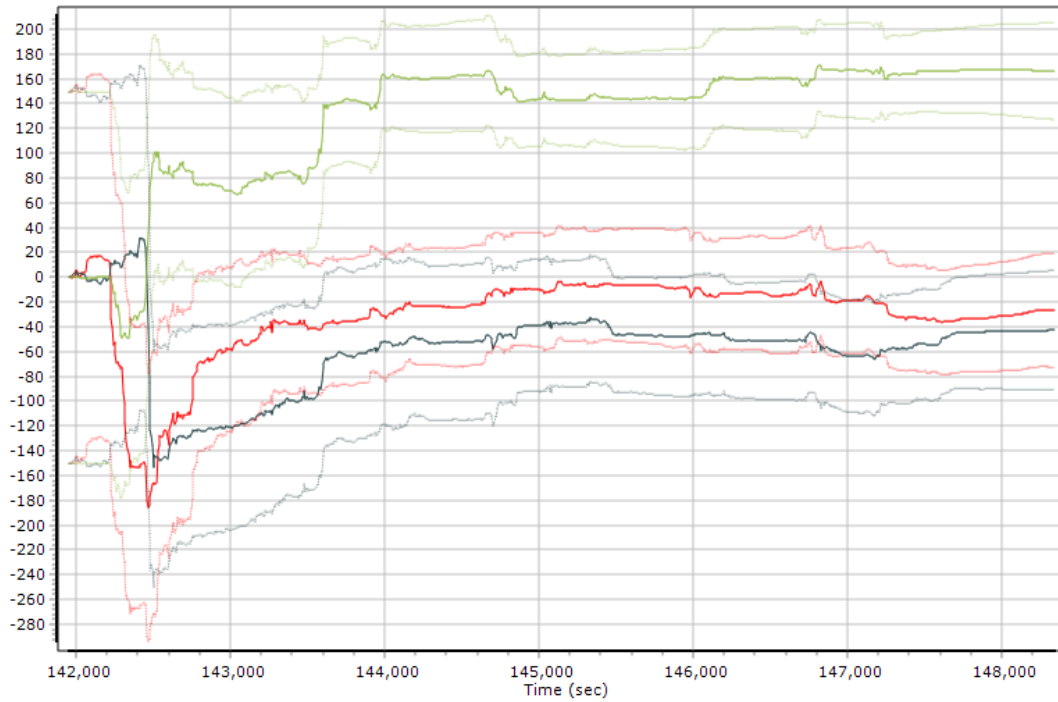


Sensor Errors



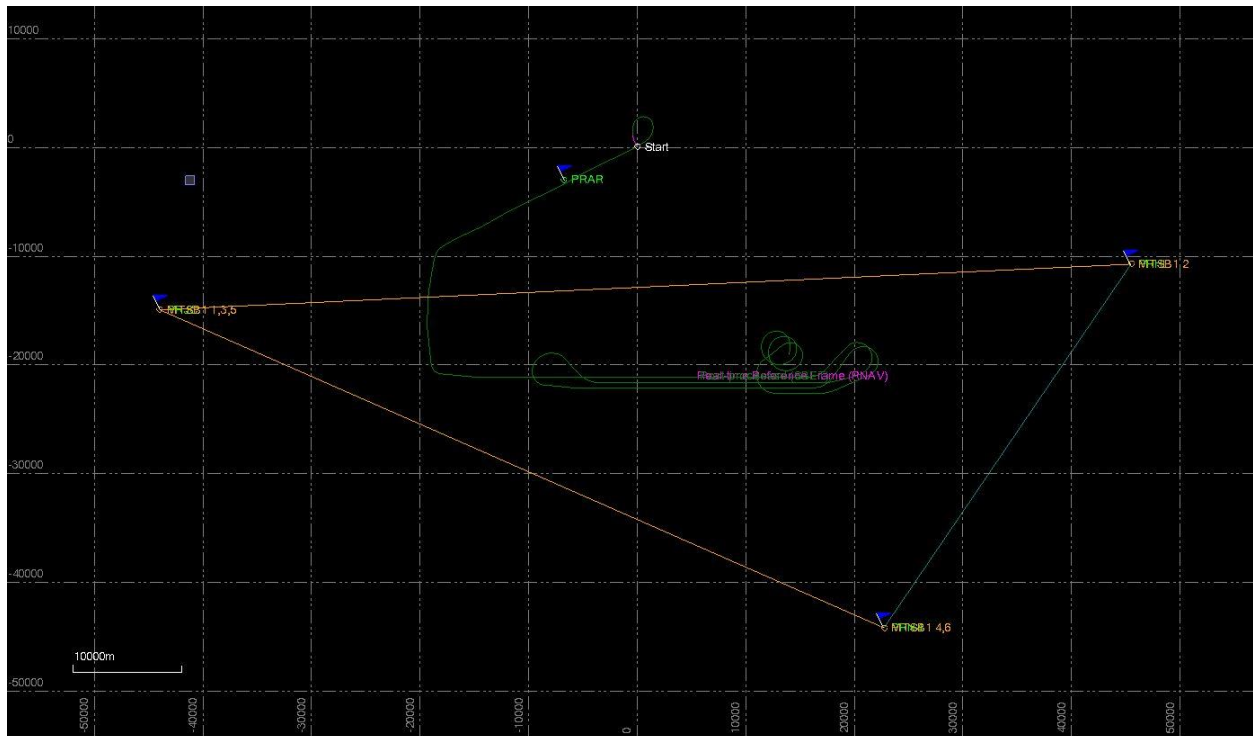


— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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

RBV18155A2



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: -0.037 m	X: 0.000 deg
Y: -0.007 m	Y: 0.000 deg
Z: -0.985 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

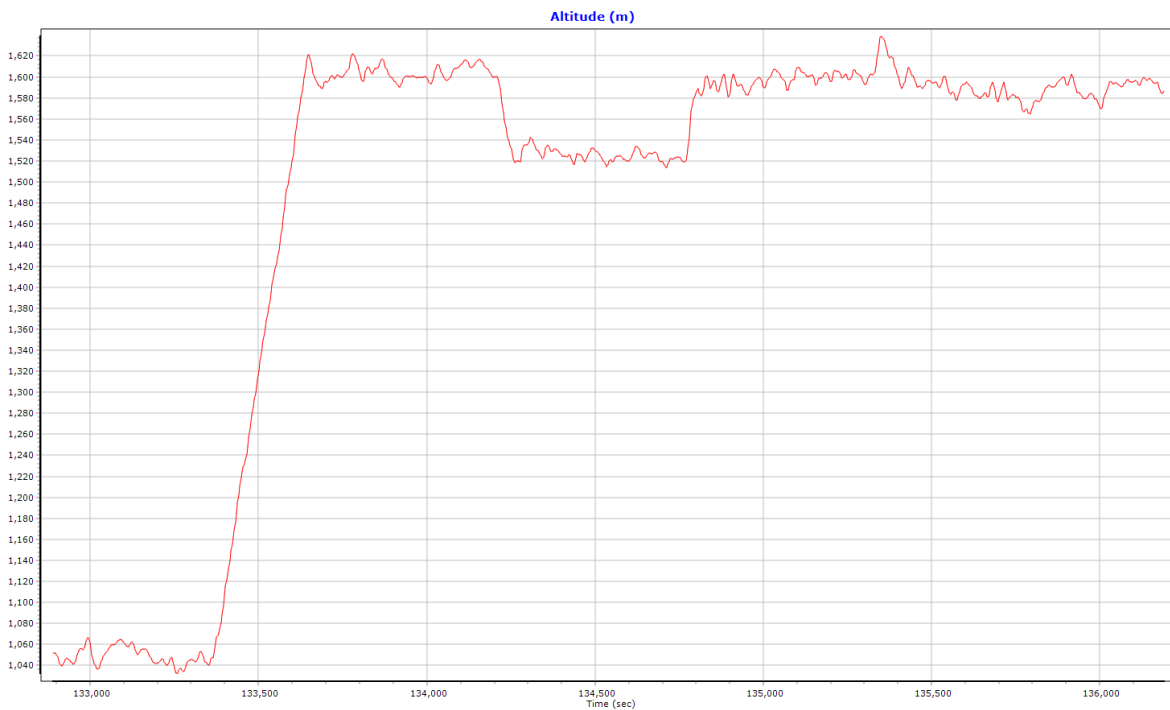
Start: 132868.000
End: 136195.000

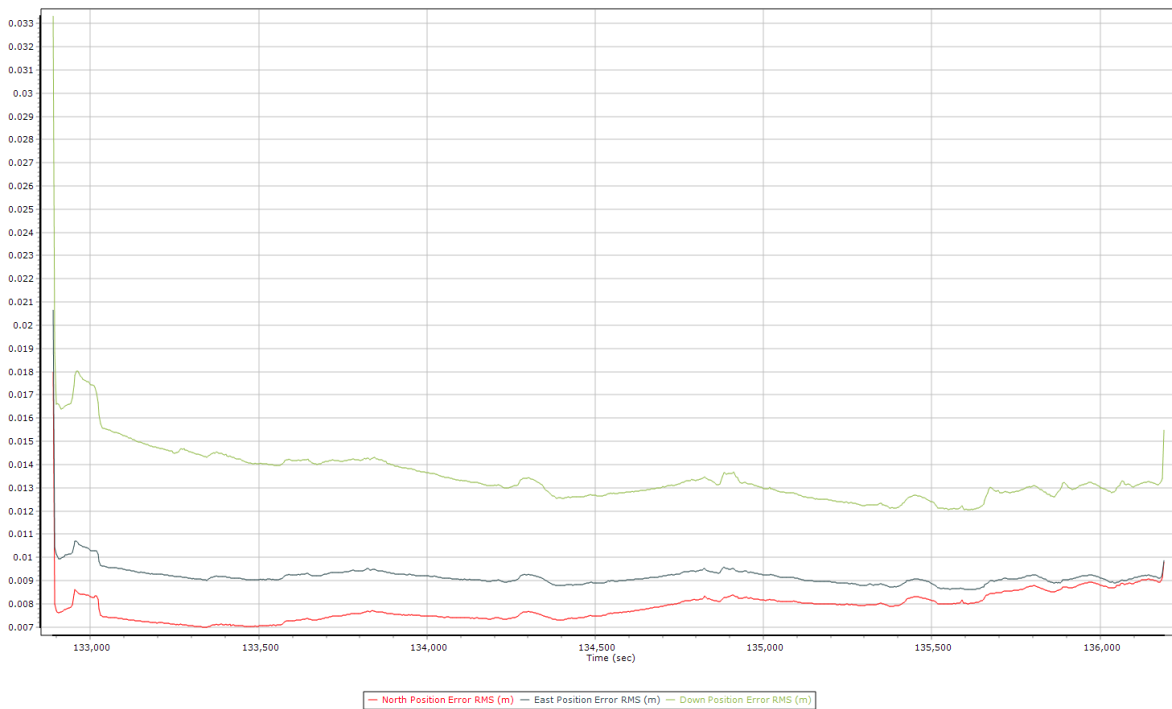
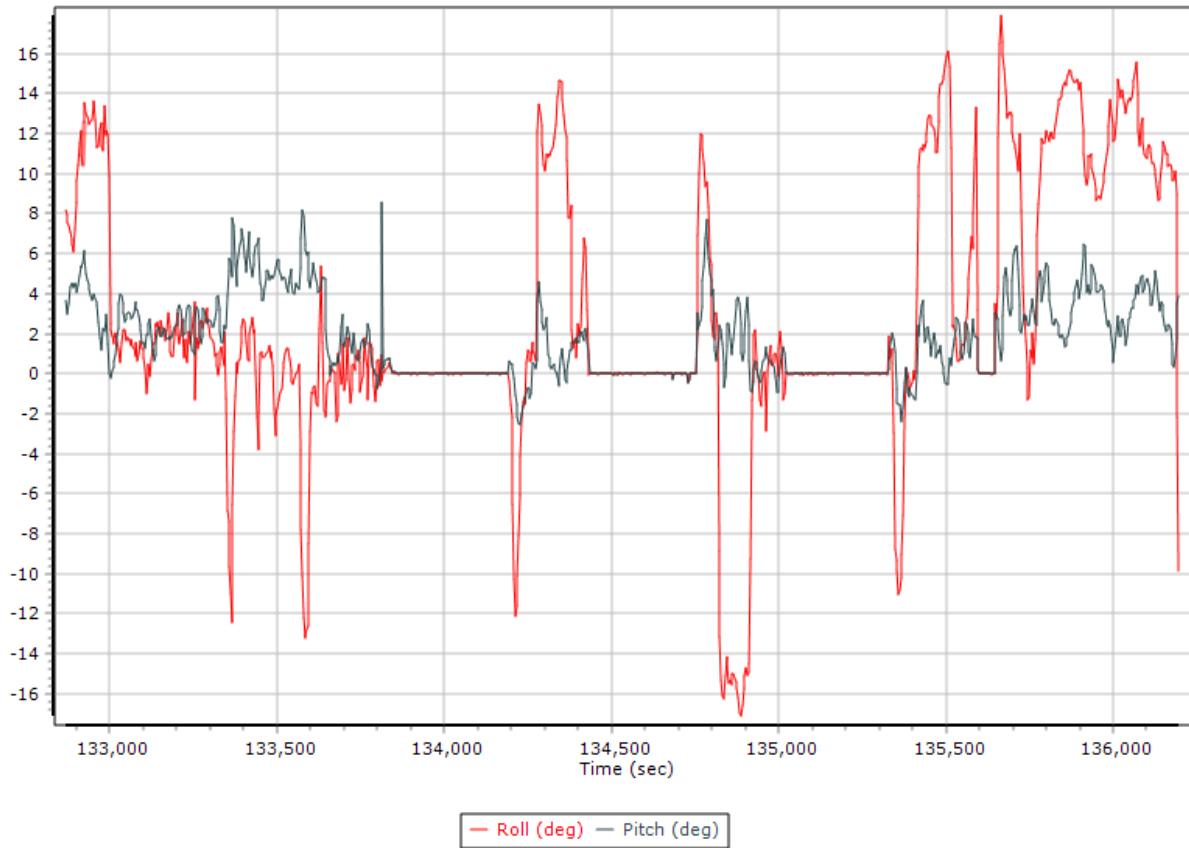
Entire time interval
 Seconds of start week

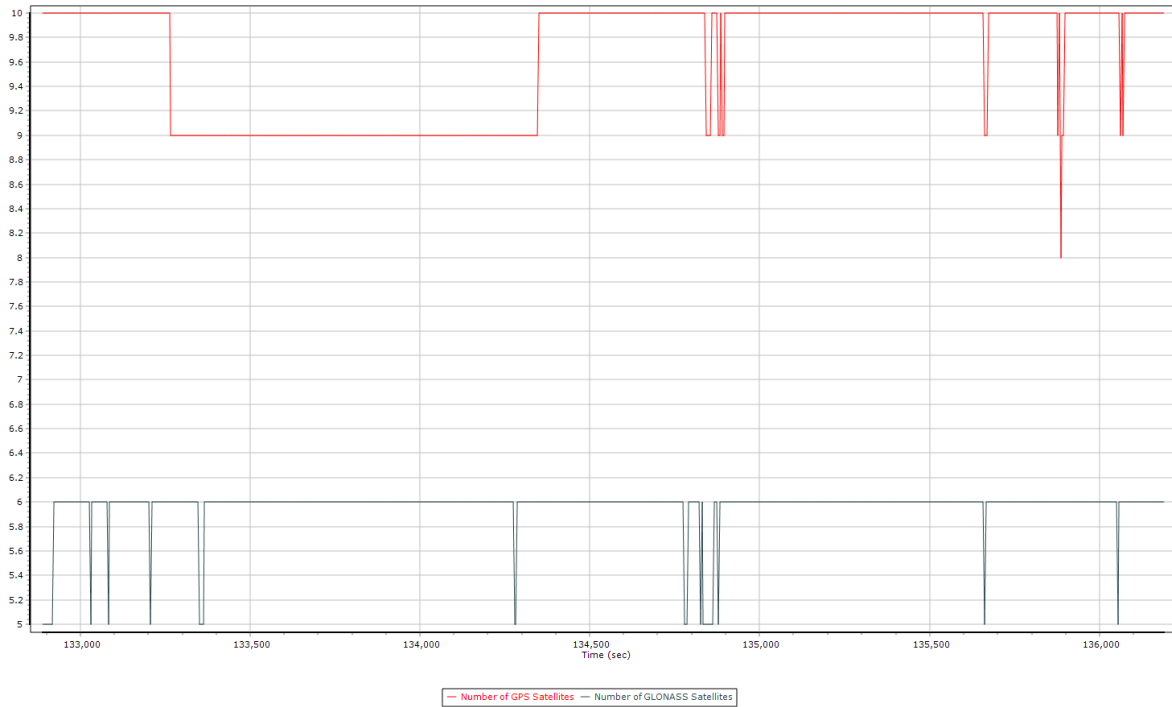
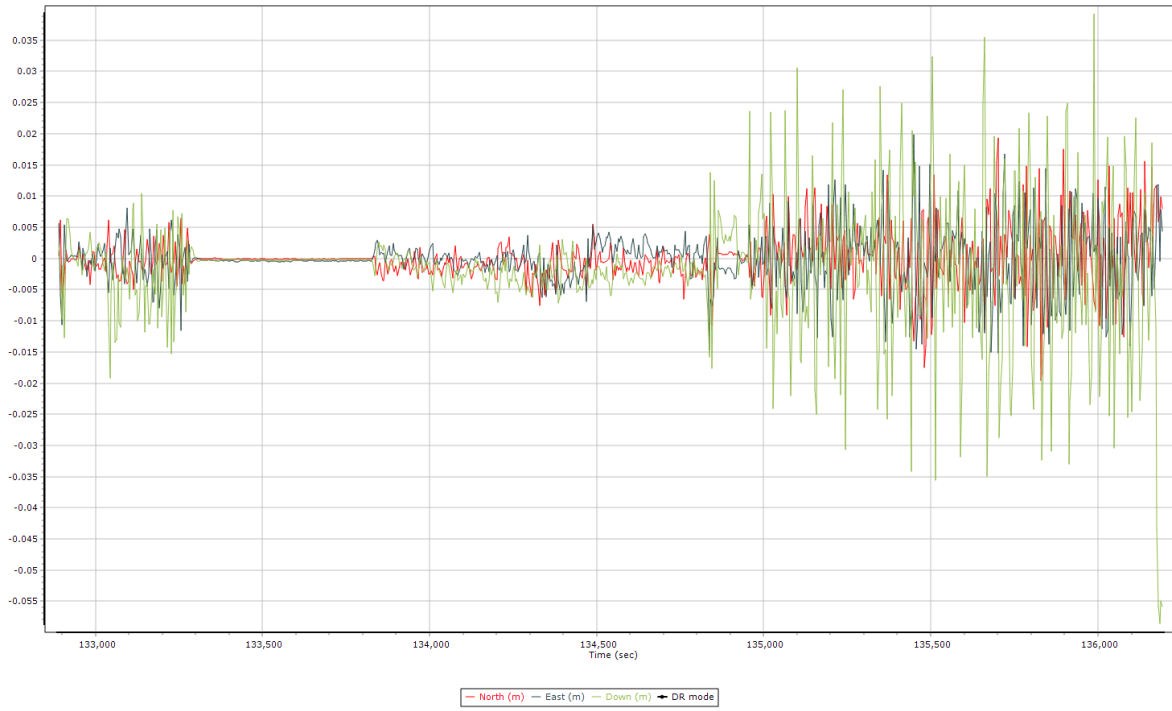
UTC Offset: 18.000

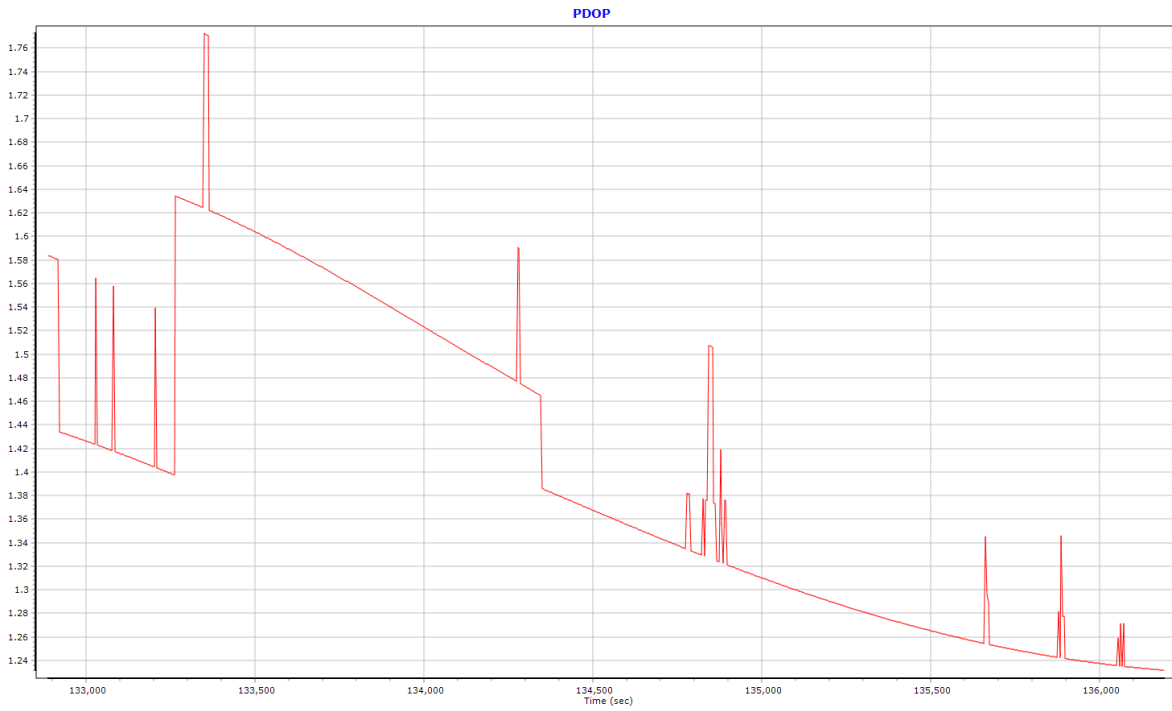
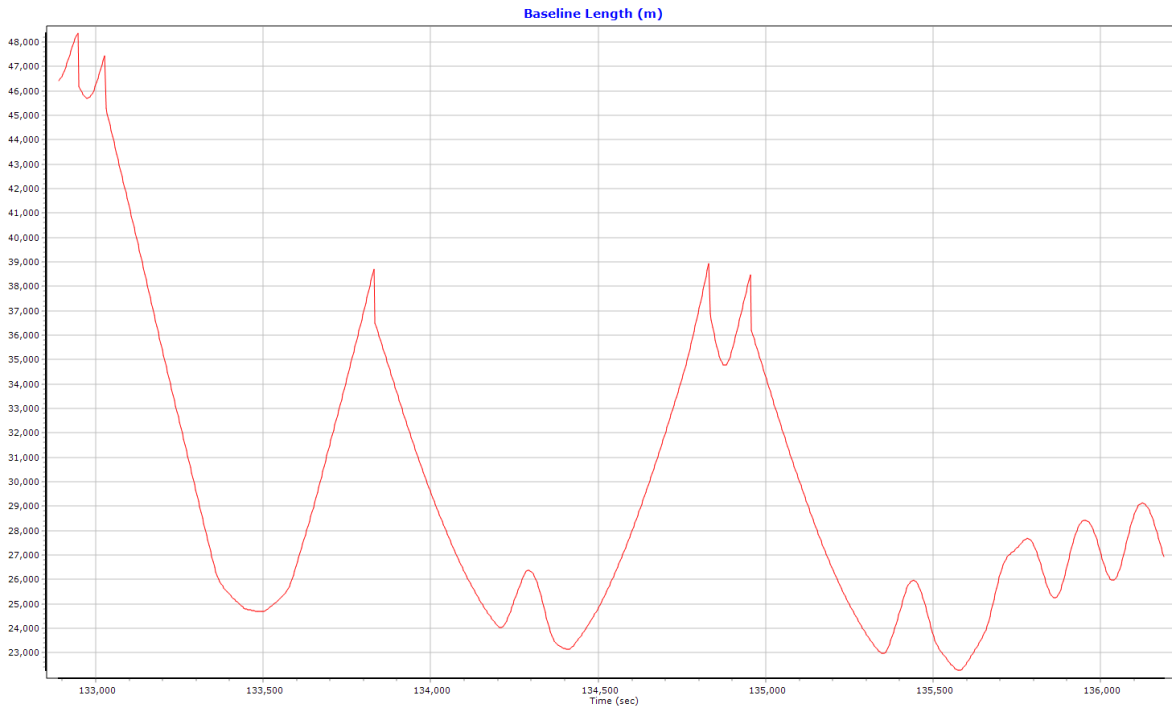
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel



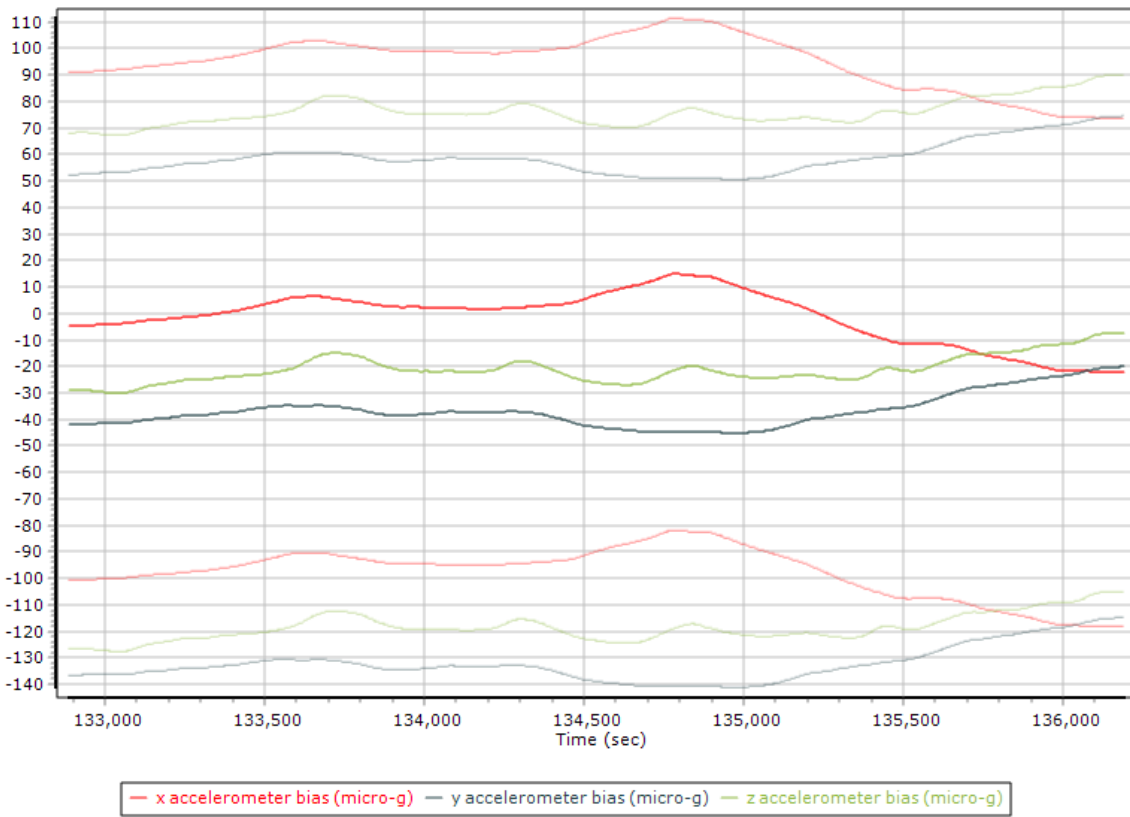


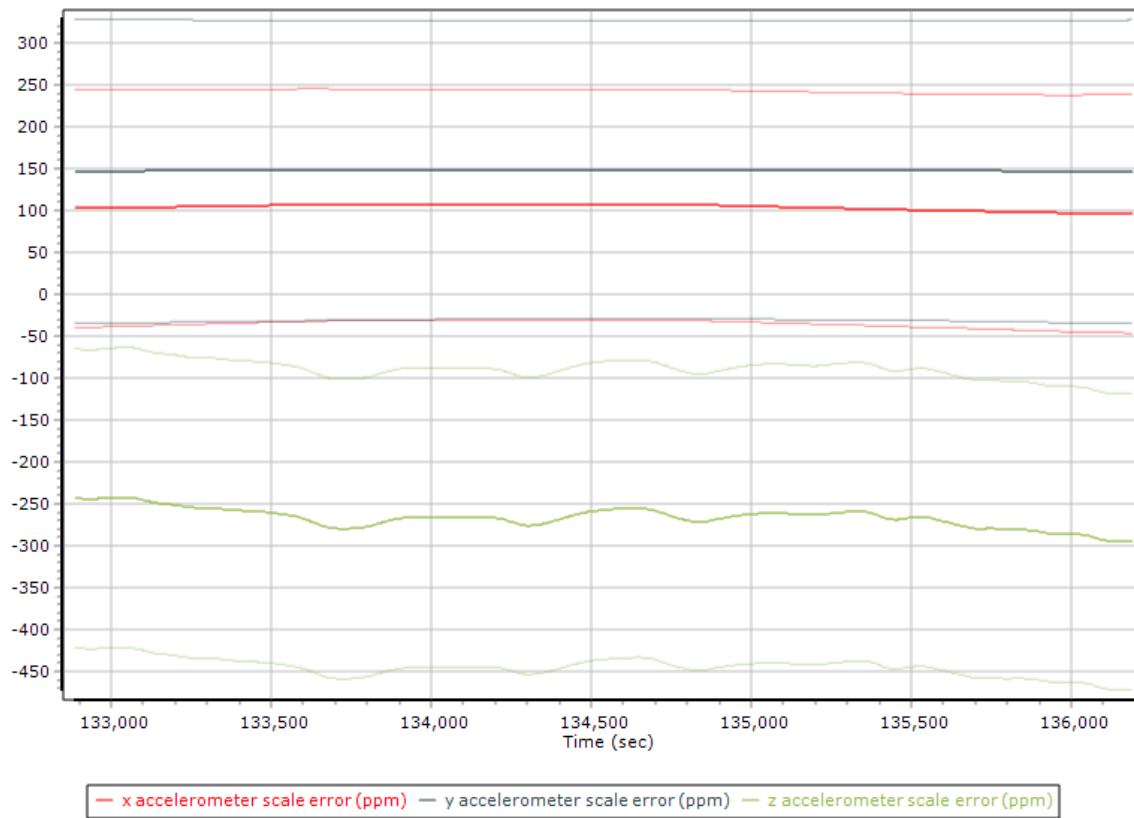


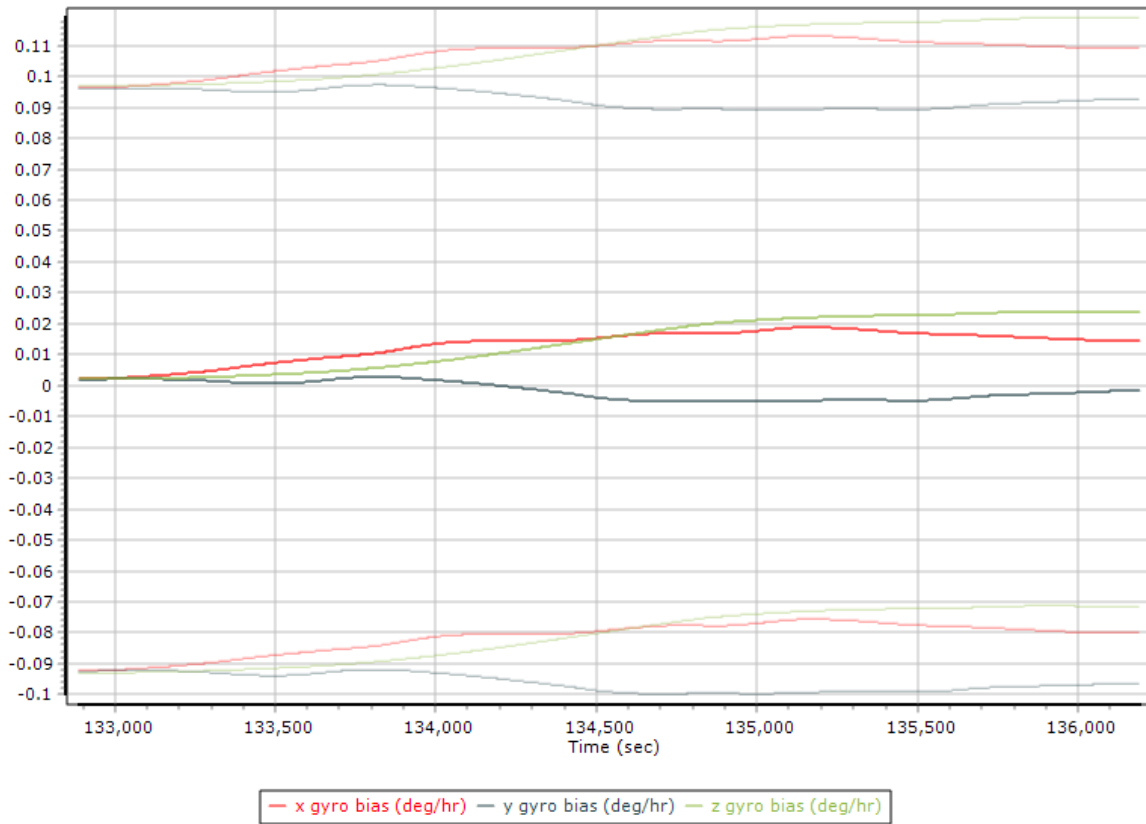


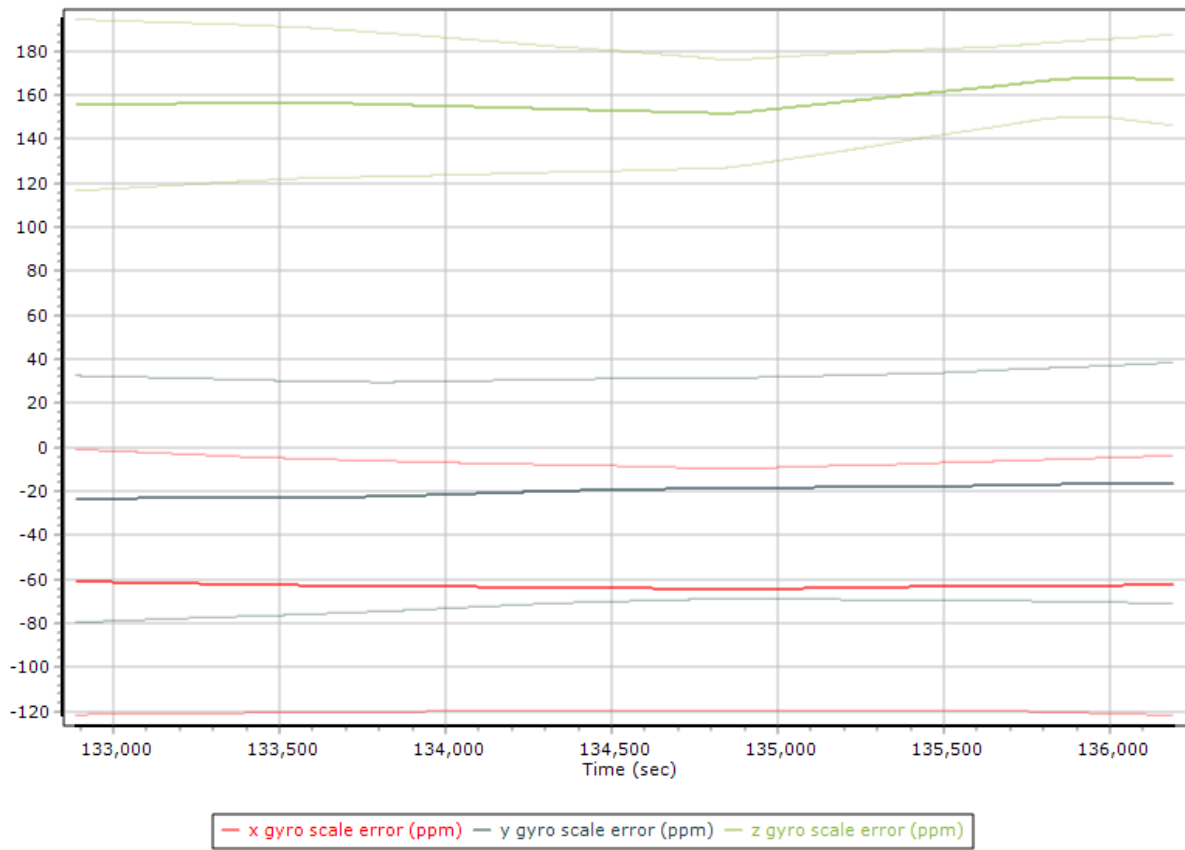


Sensor Errors

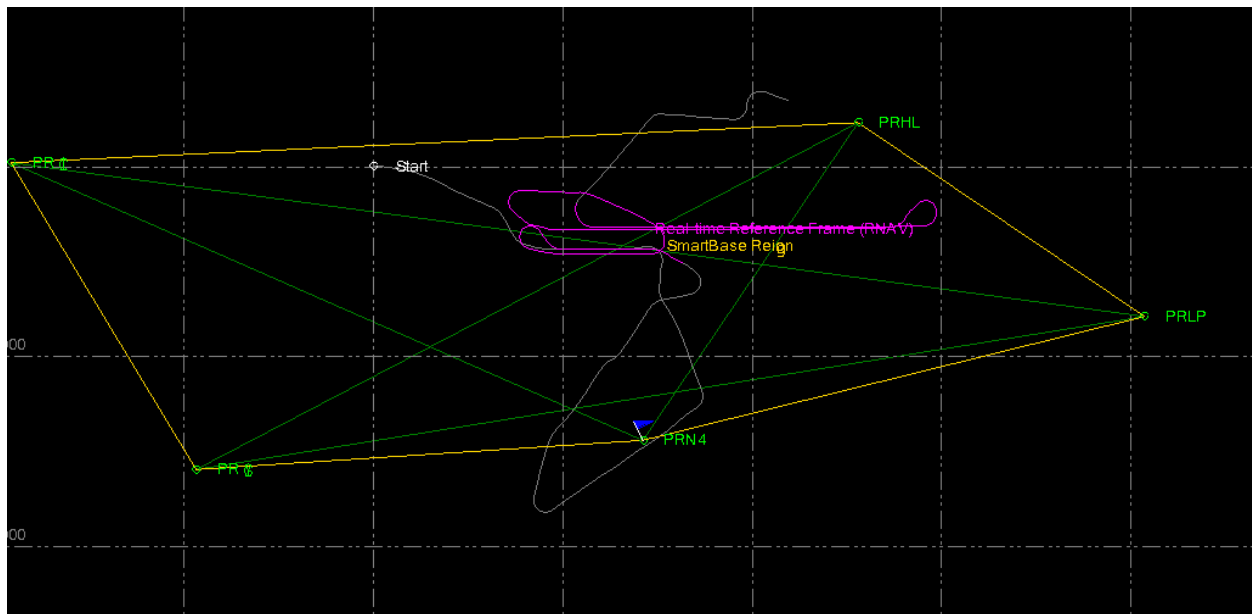








RBV18155B



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: -0.034 m
Y: -0.010 m
Z: -0.352 m

Stabilized Mount to IMU Mounting Angles
X: 0.000 deg
Y: 0.000 deg
Z: 0.000 deg

Stabilized Mount to Primary GNSS Lever Arm
X: -0.037 m
Y: 0.007 m
Z: -0.985 m

Aircraft to Stabilized Mount Mounting Angles
X: 0.000 deg
Y: 0.000 deg
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

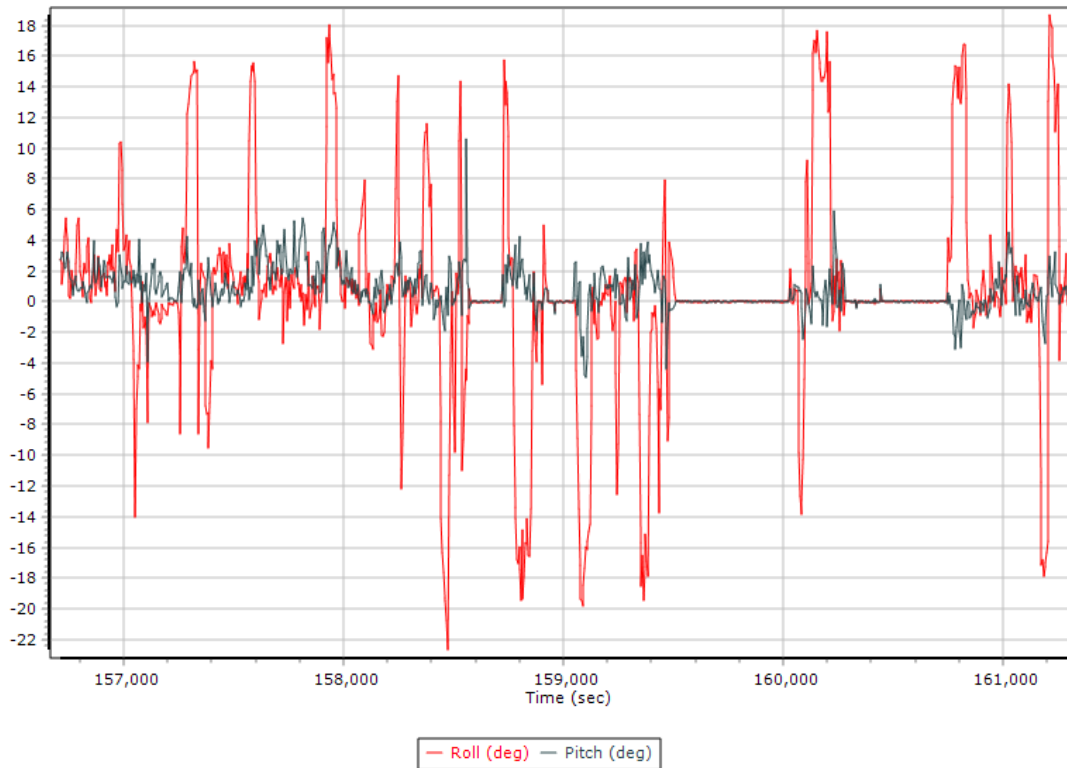
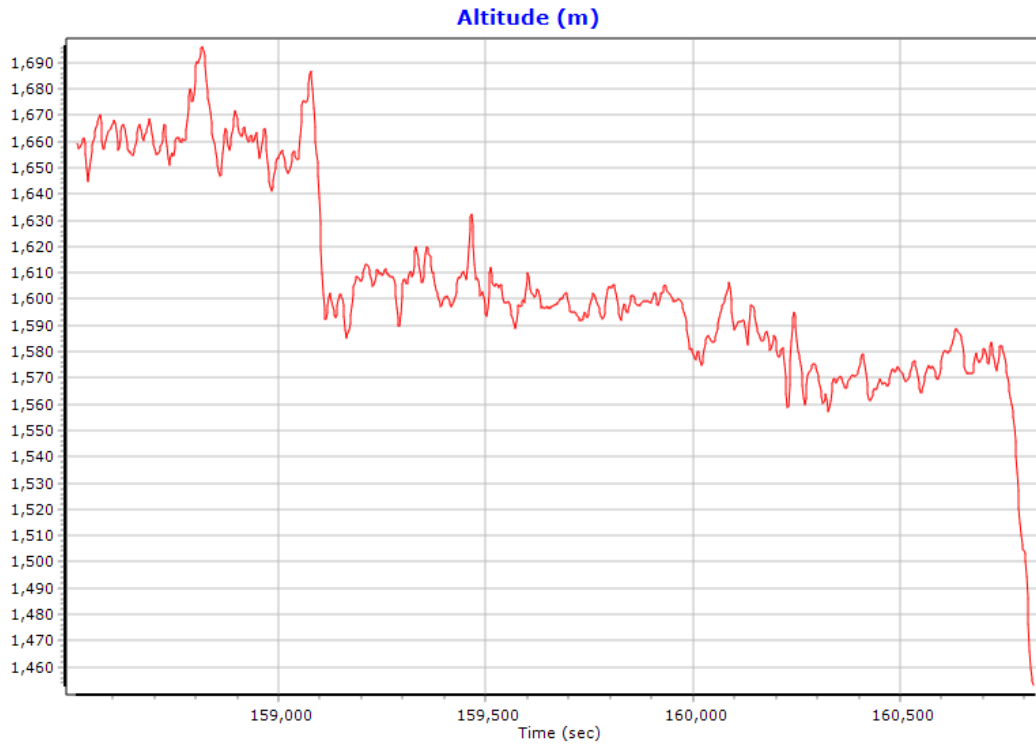
Project Settings

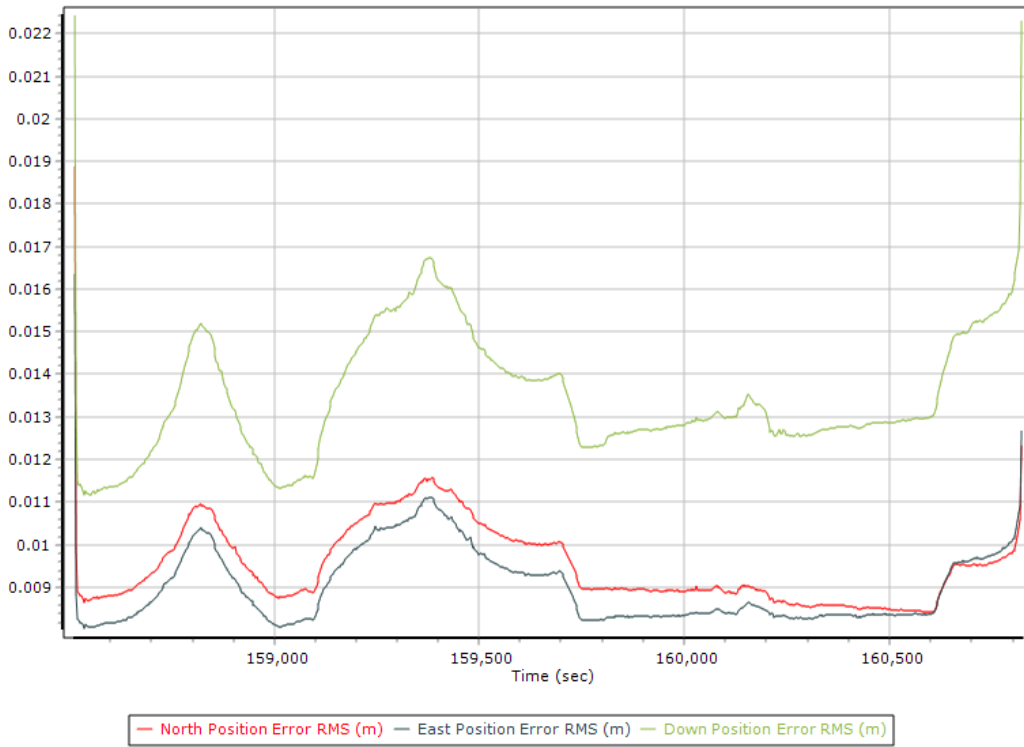
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
Timing
Algorithms
Initialization
Lever Arms and Mounting Angles
Export
Camera
LiDAR
SAR

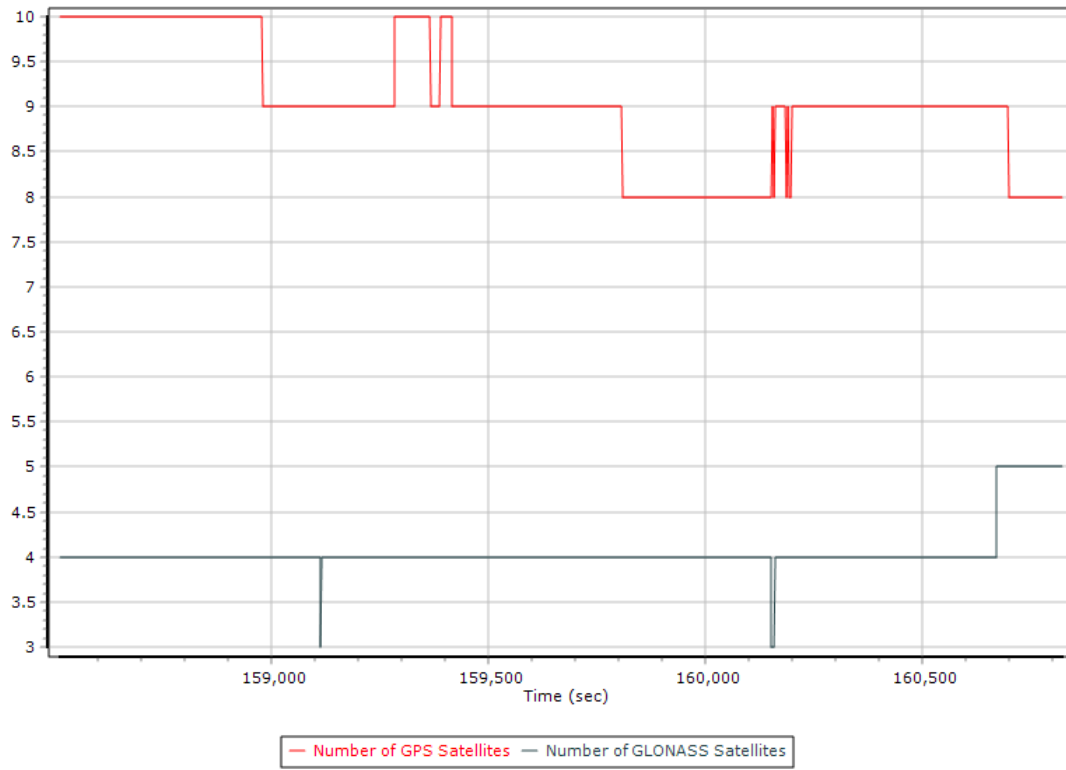
Timing
Start: 158512.148
End: 160825.697
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

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

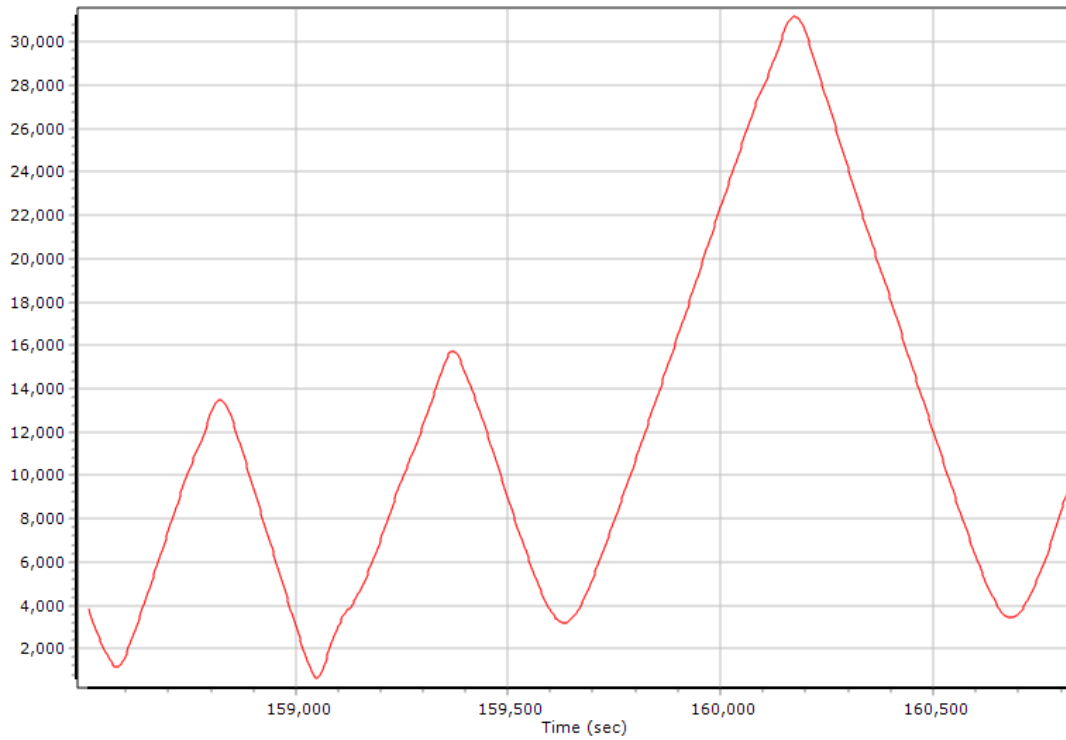
OK Cancel



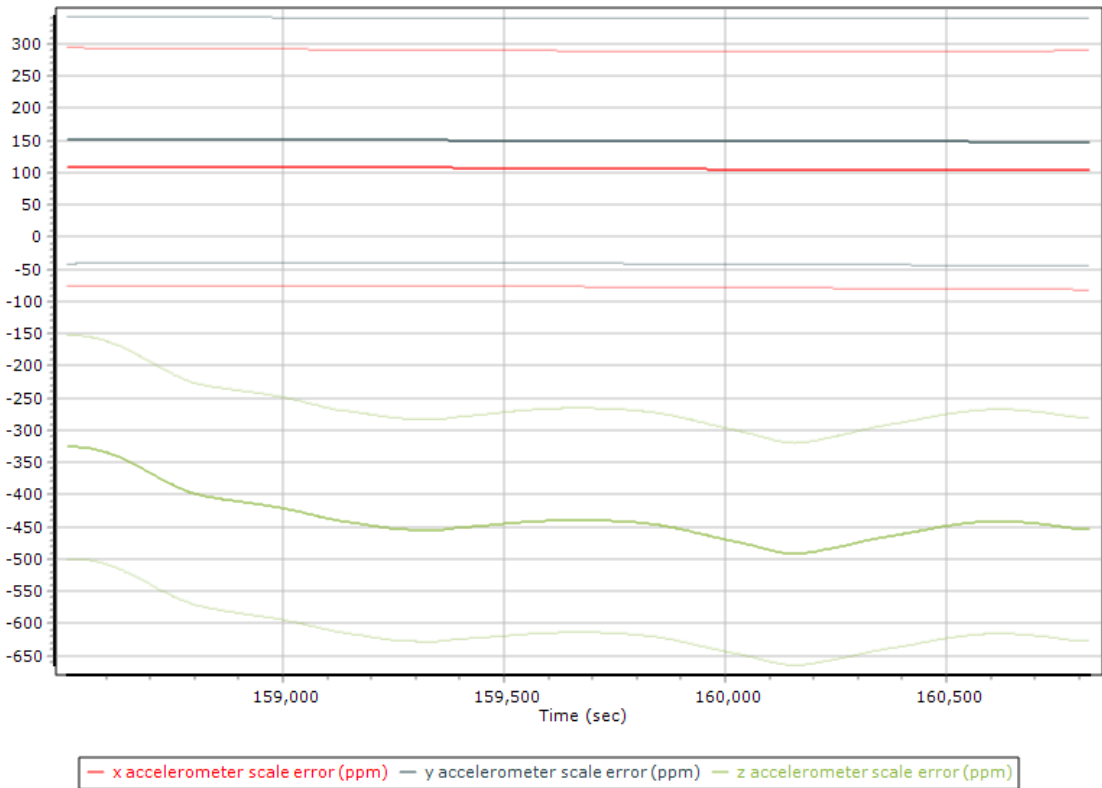
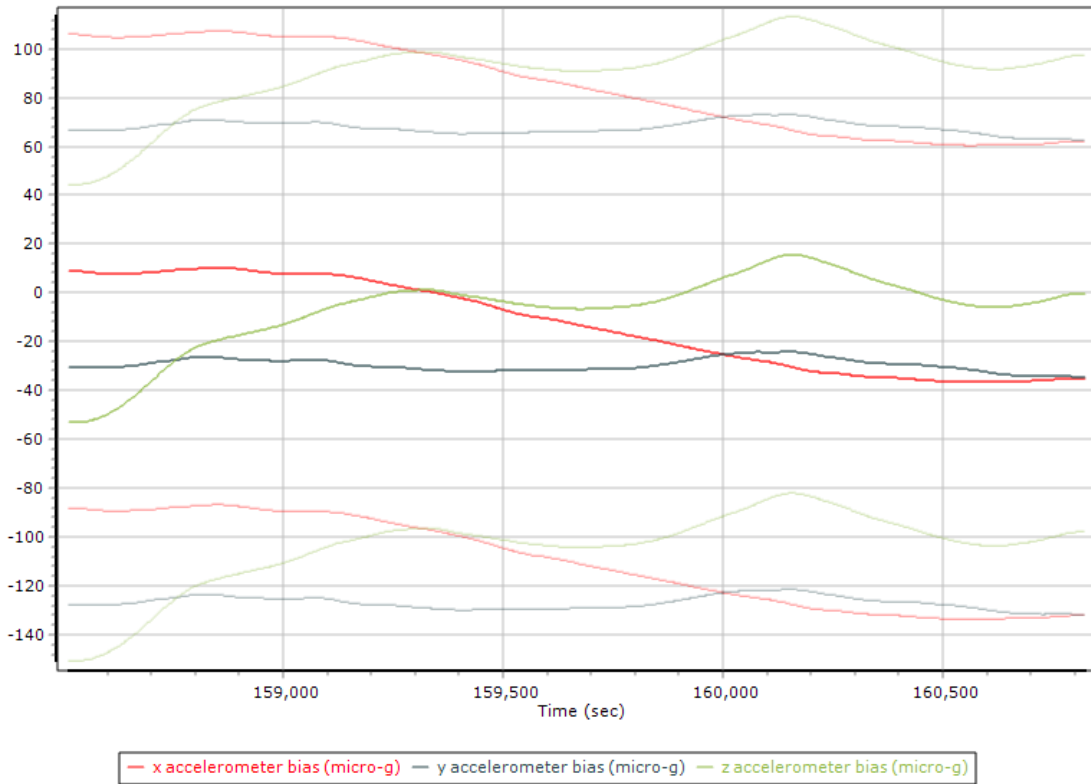


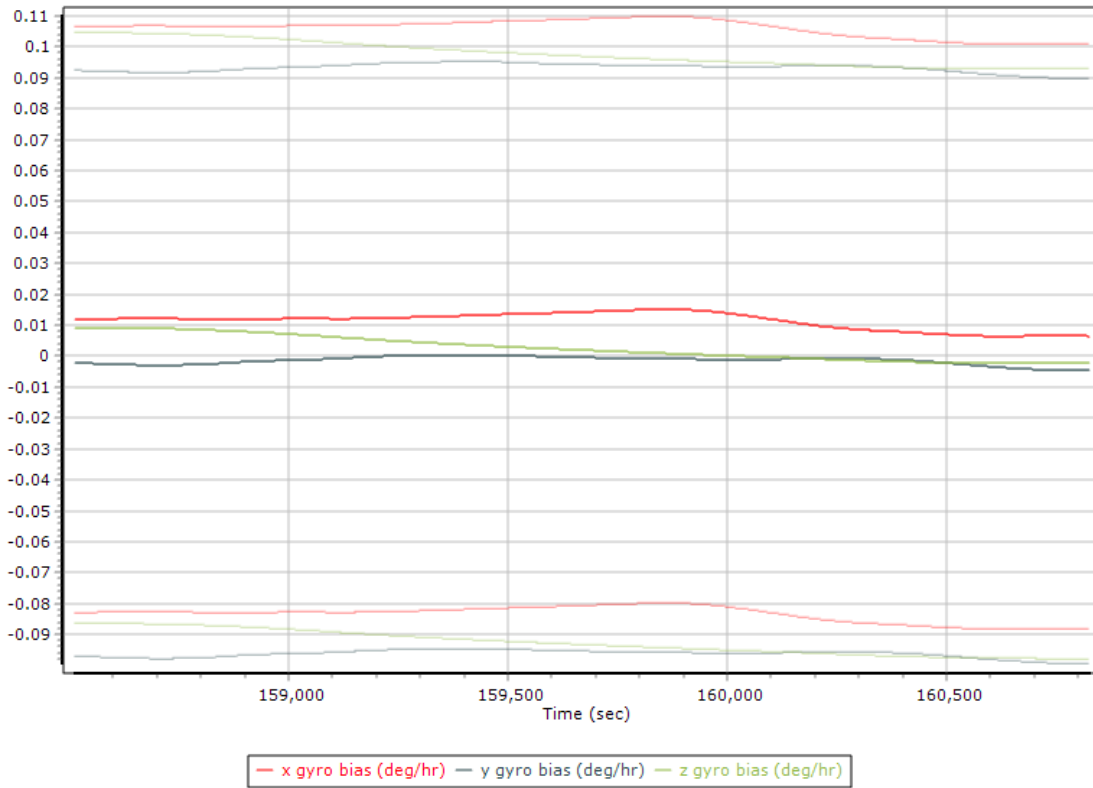


Baseline Length (m)

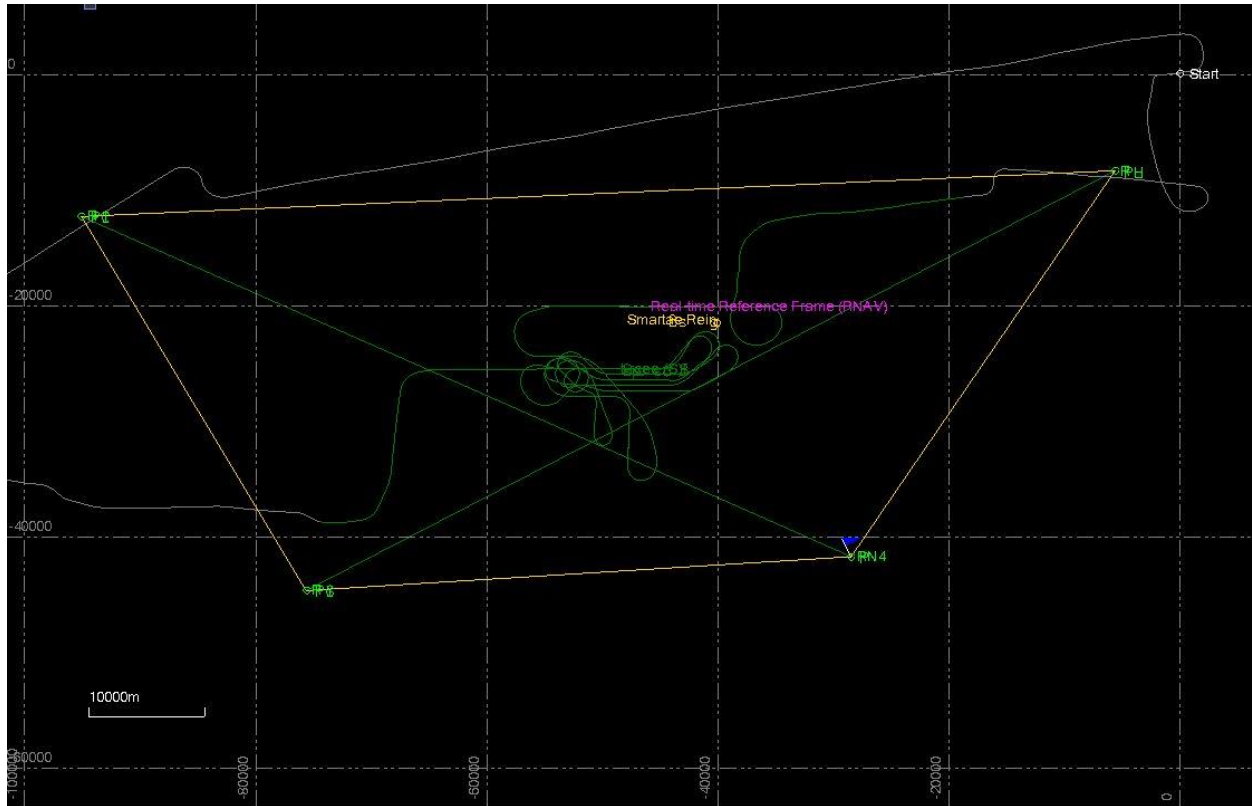


Sensor Errors





RBV18160A



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

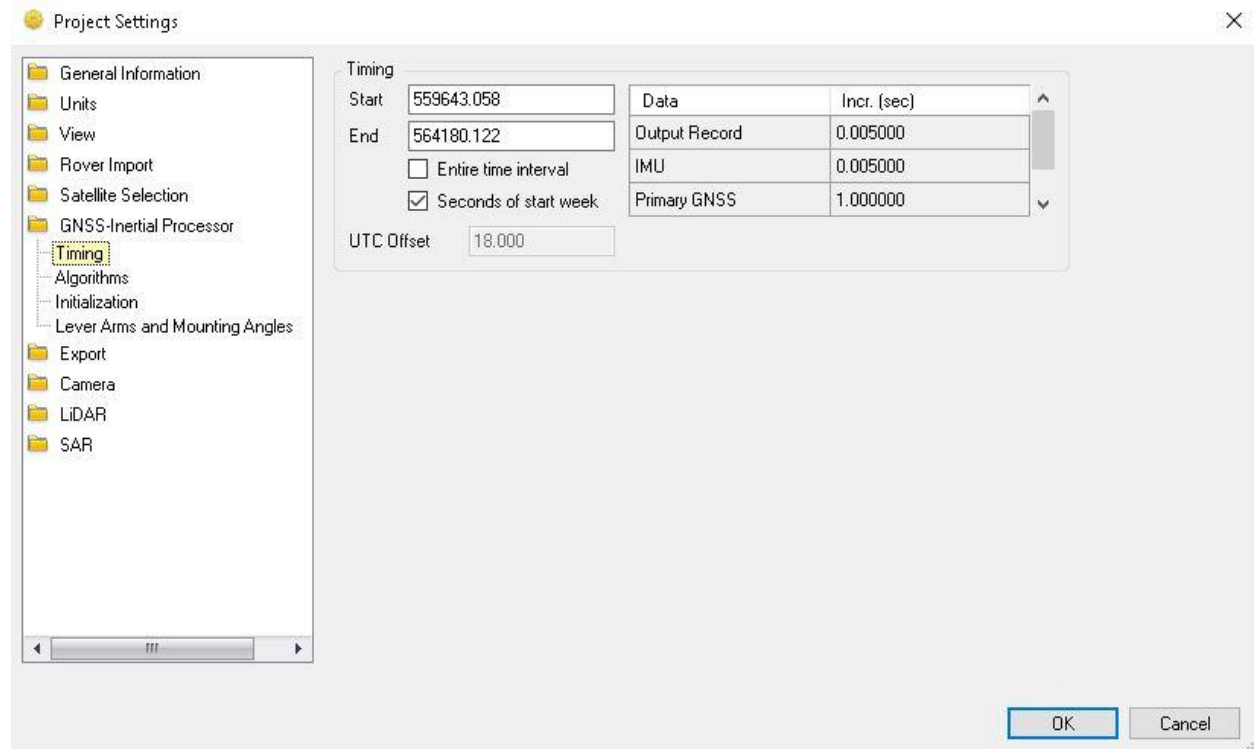
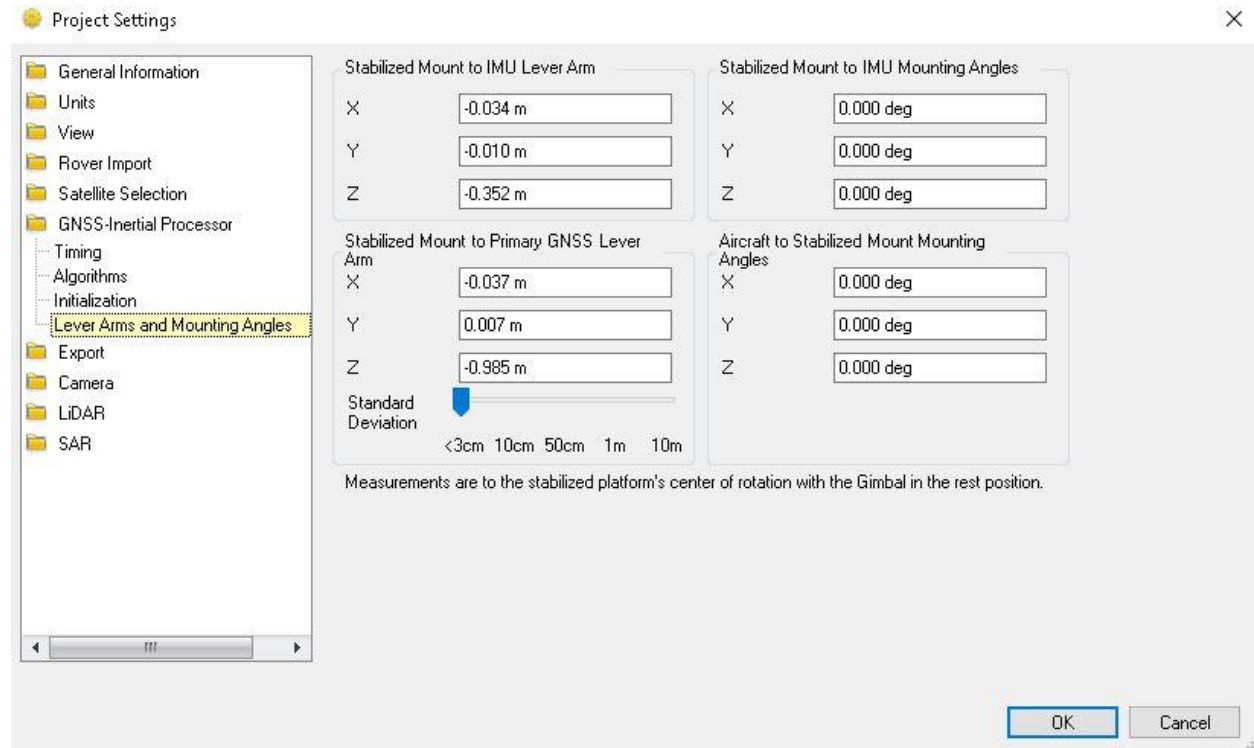
Stabilized Mount to IMU Lever Arm	Stabilized Mount to IMU Mounting Angles
X: -0.034 m	X: 0.000 deg
Y: -0.010 m	Y: 0.000 deg
Z: -0.352 m	Z: 0.000 deg

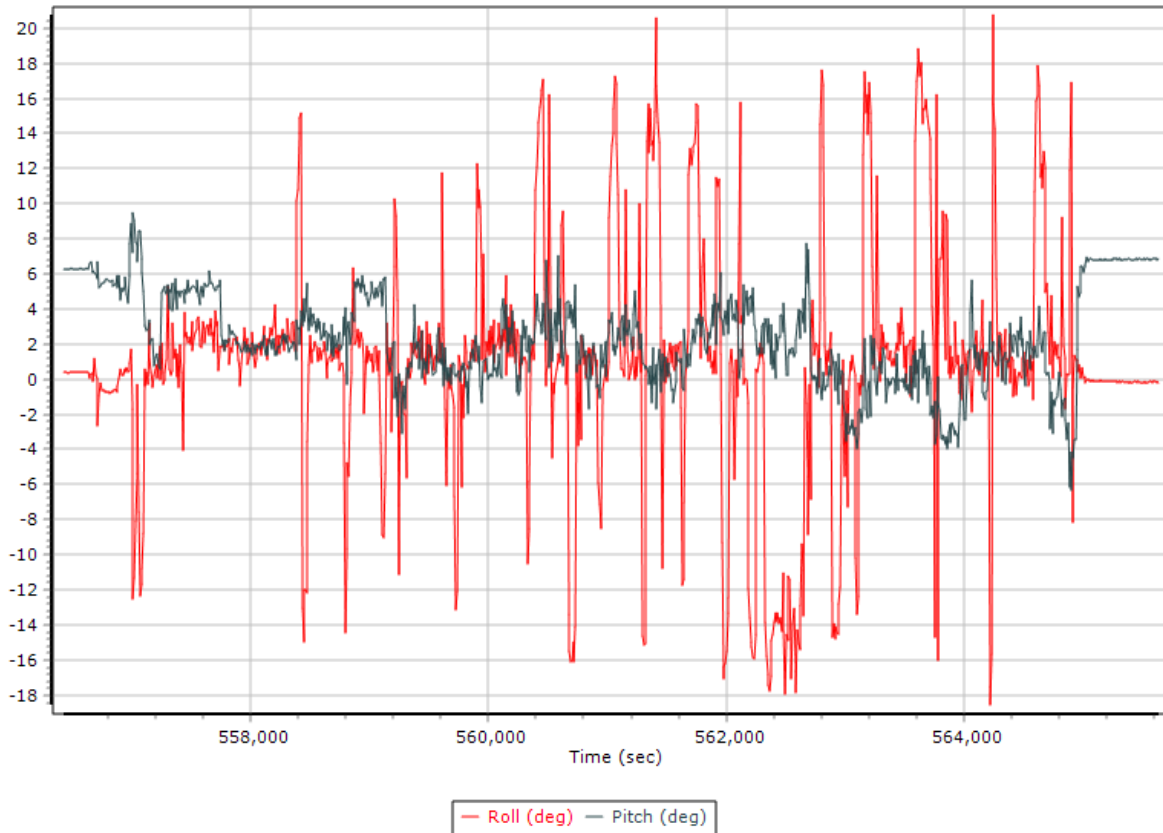
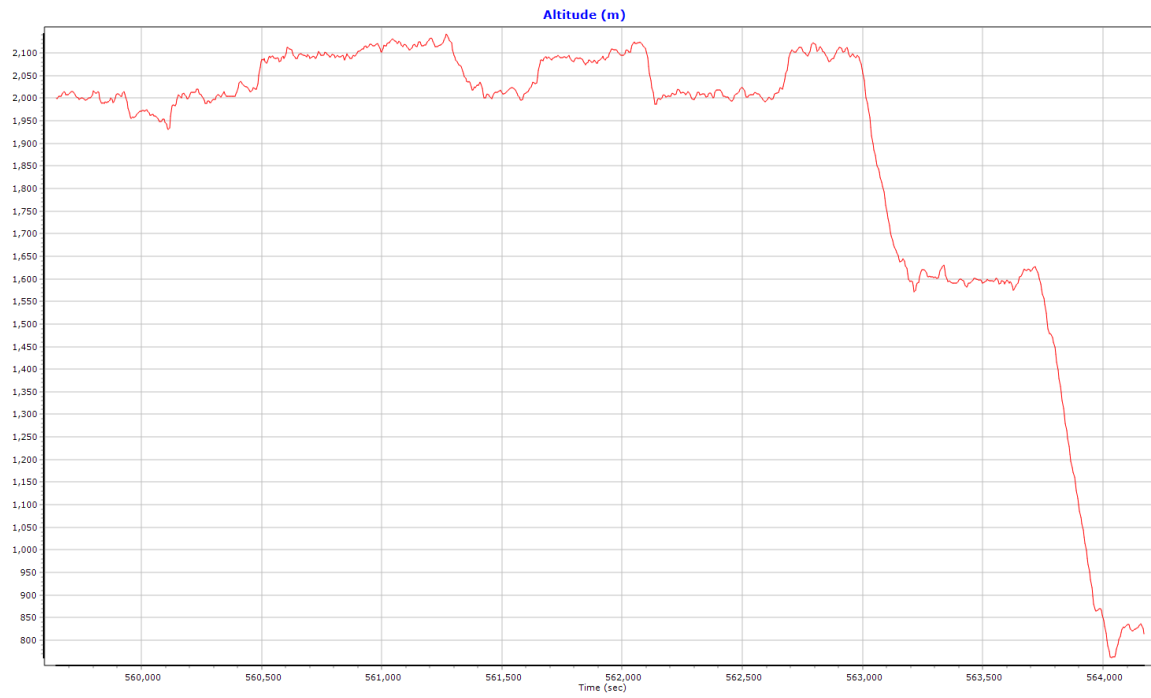
Stabilized Mount to Primary GNSS Lever Arm	Aircraft to Stabilized Mount Mounting Angles
X: -0.037 m	X: 0.000 deg
Y: 0.007 m	Y: 0.000 deg
Z: -0.985 m	Z: 0.000 deg

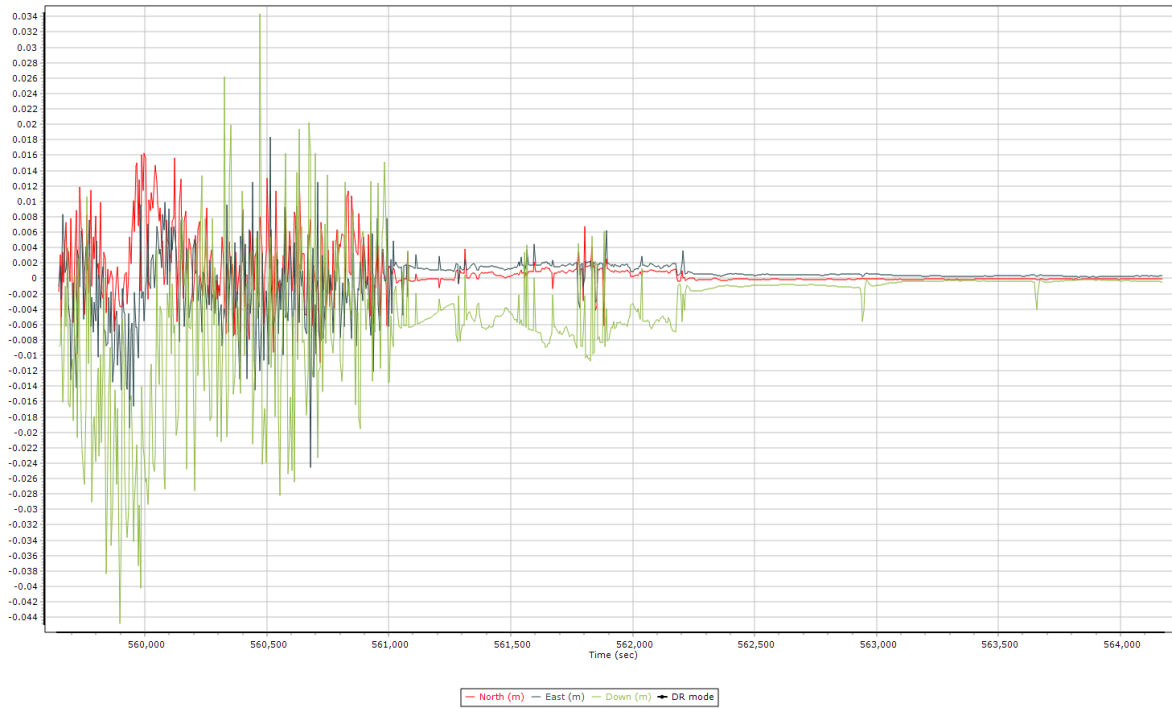
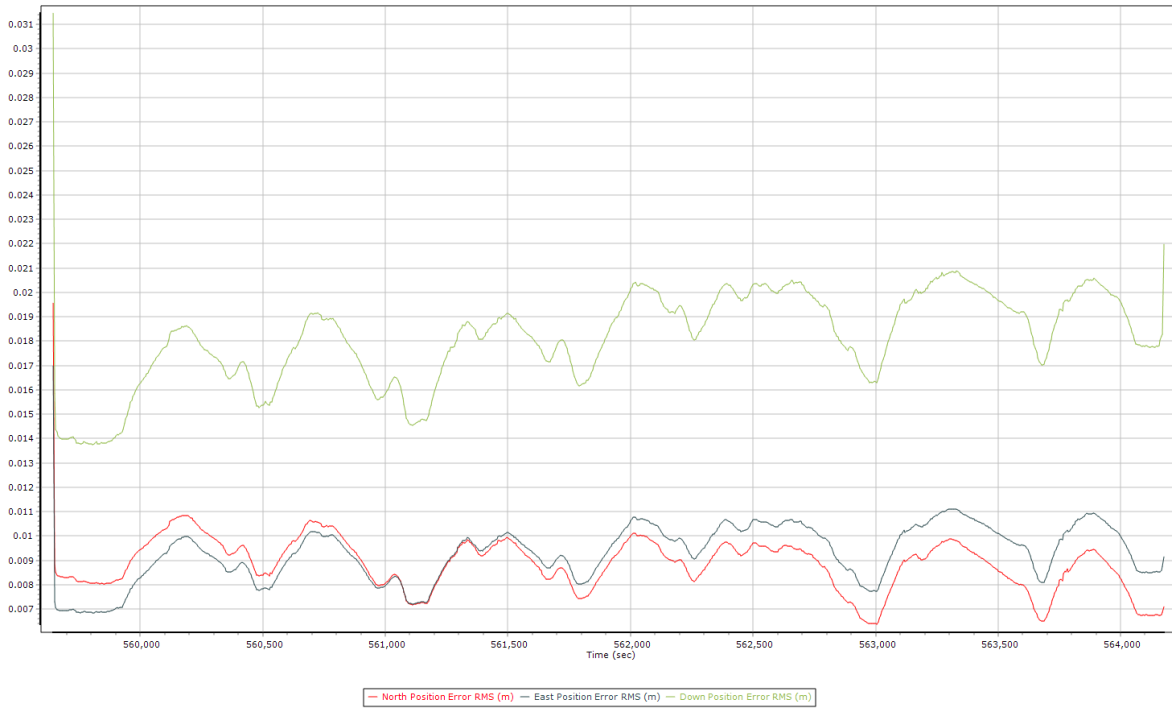
Standard Deviation: <3cm 10cm 50cm 1m 10m

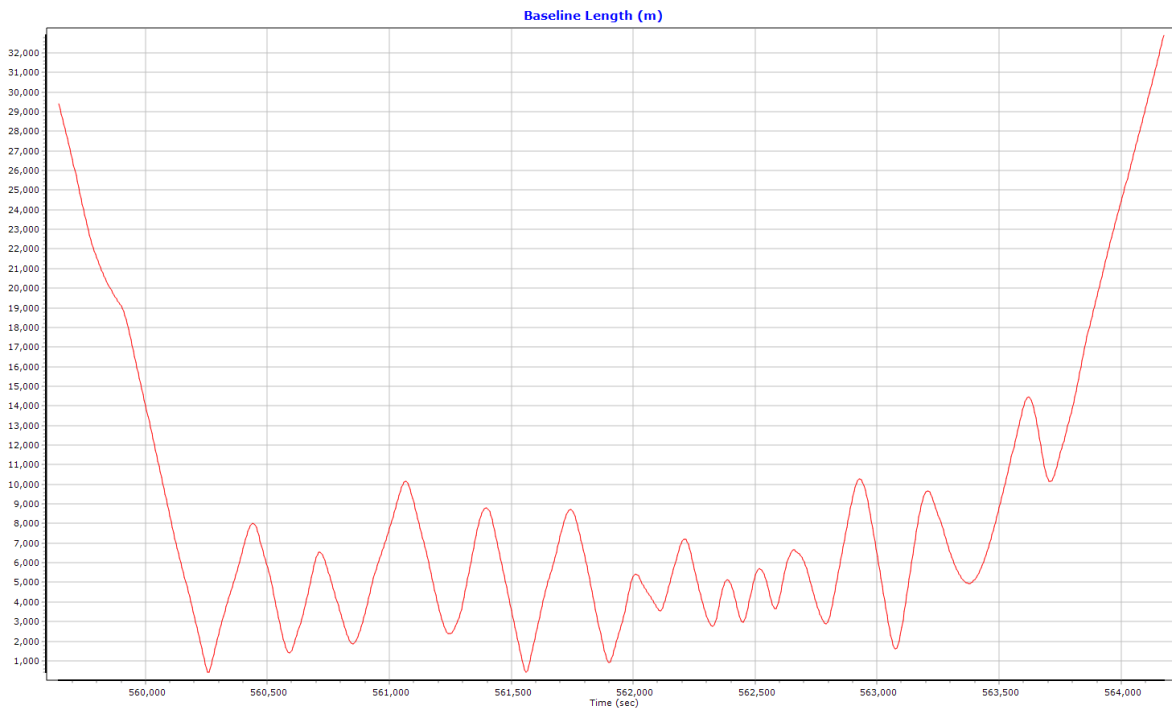
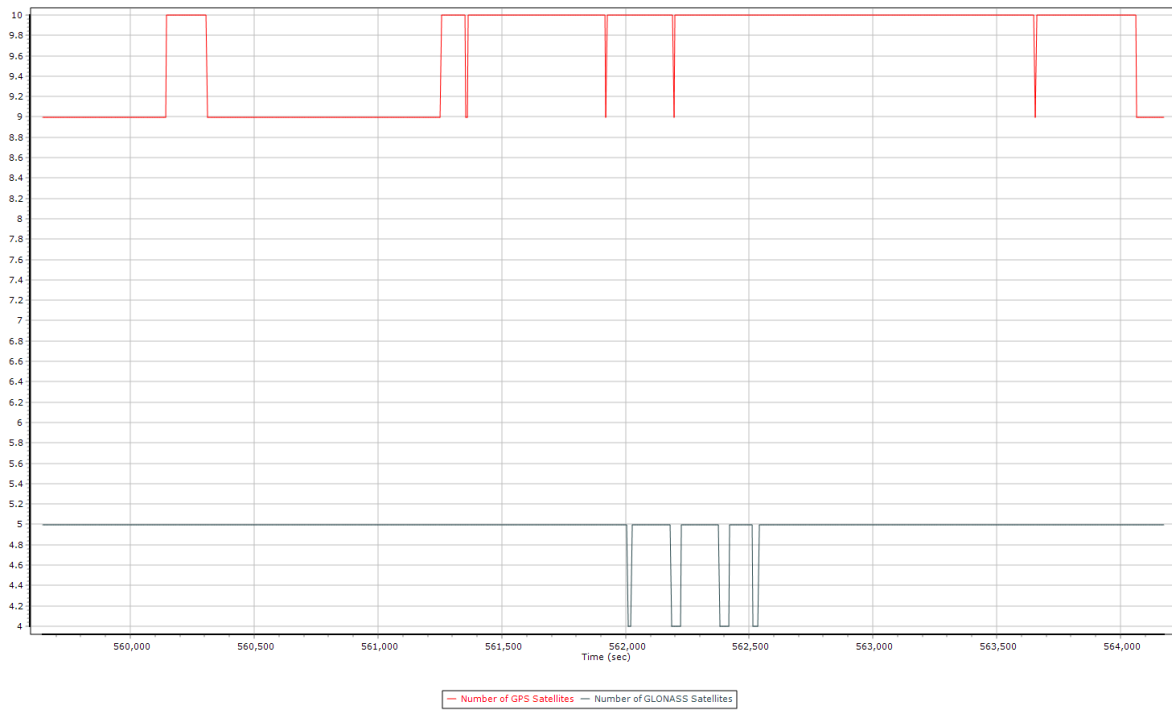
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

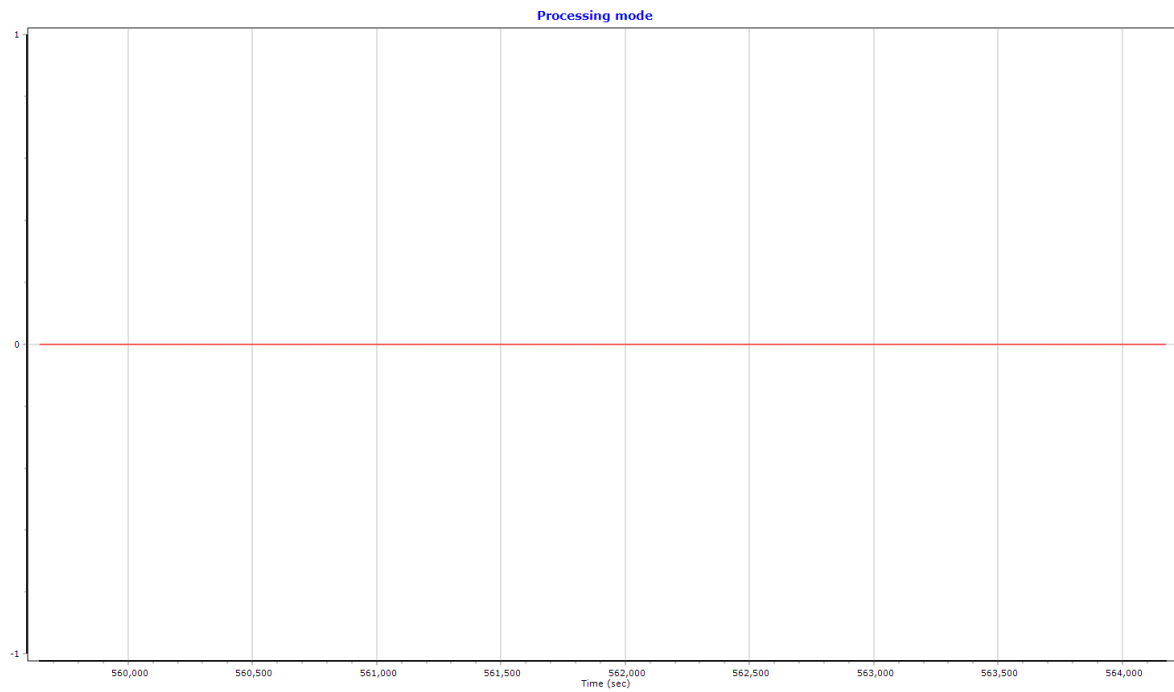
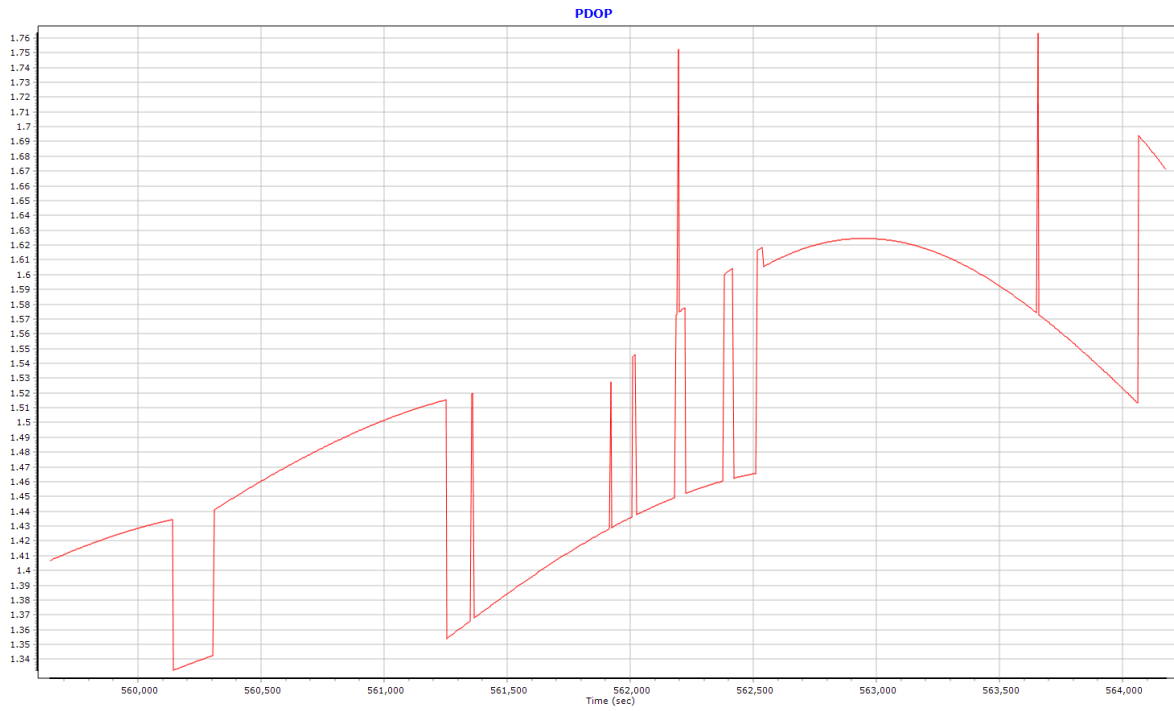
OK Cancel







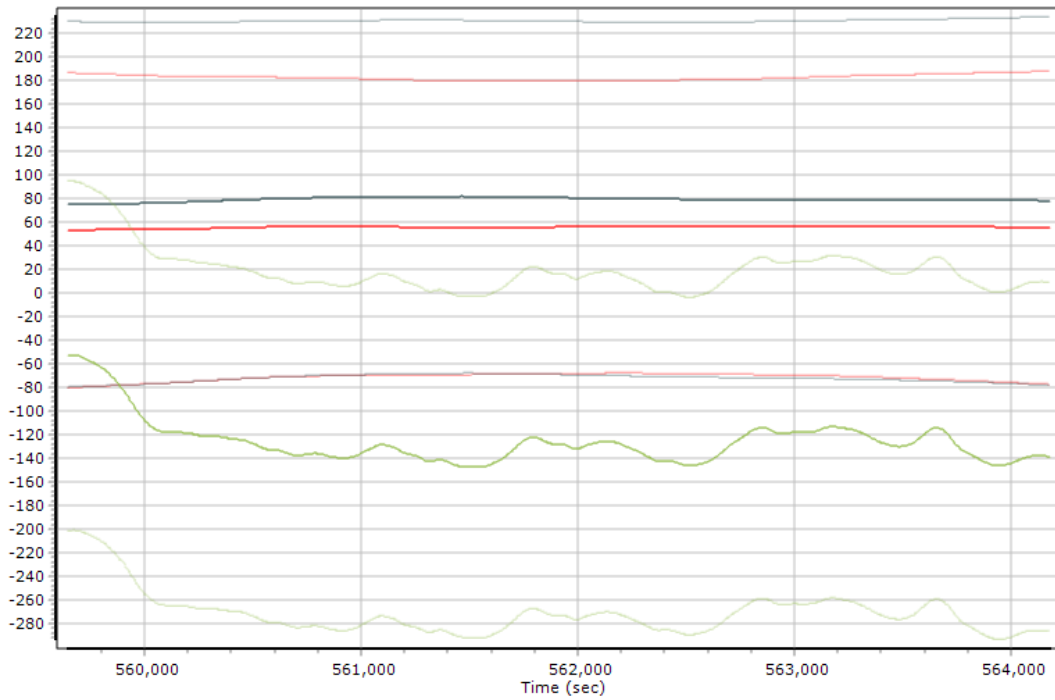




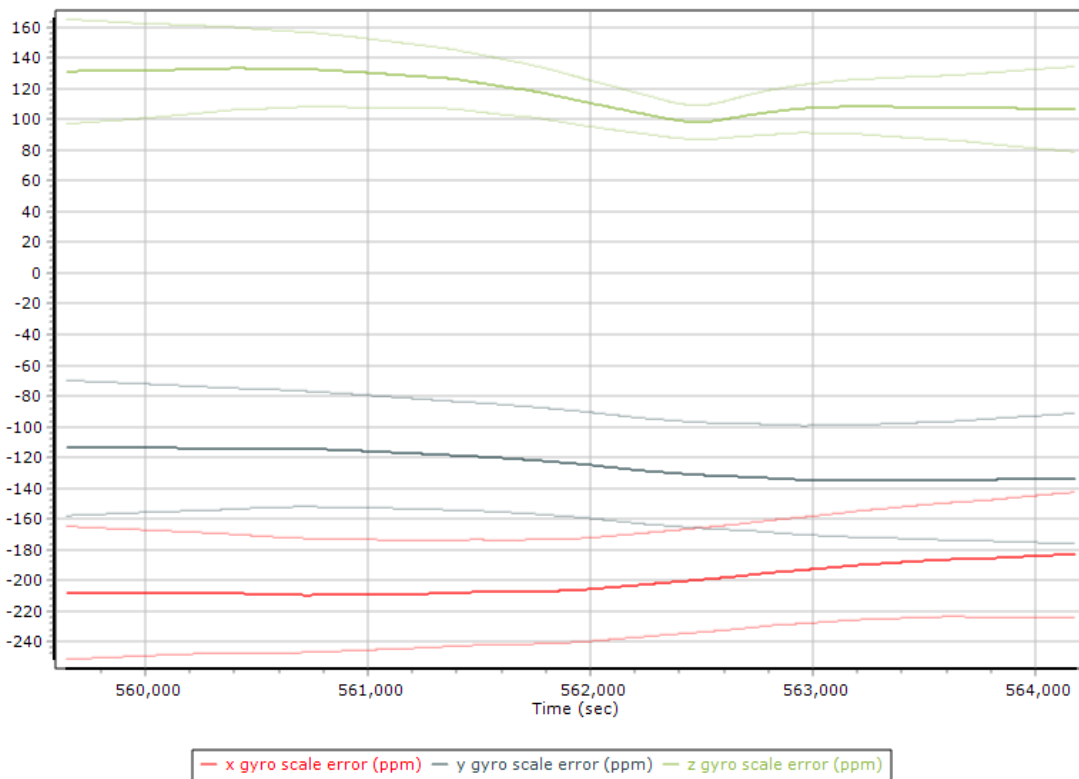
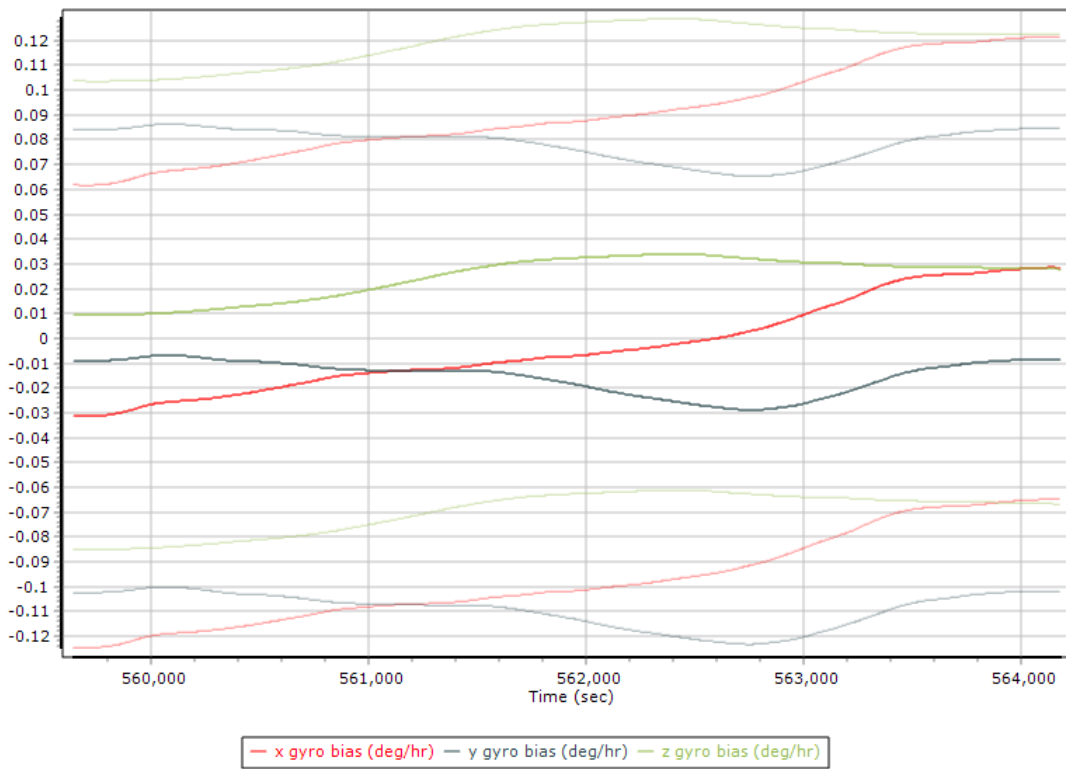
Sensor Errors



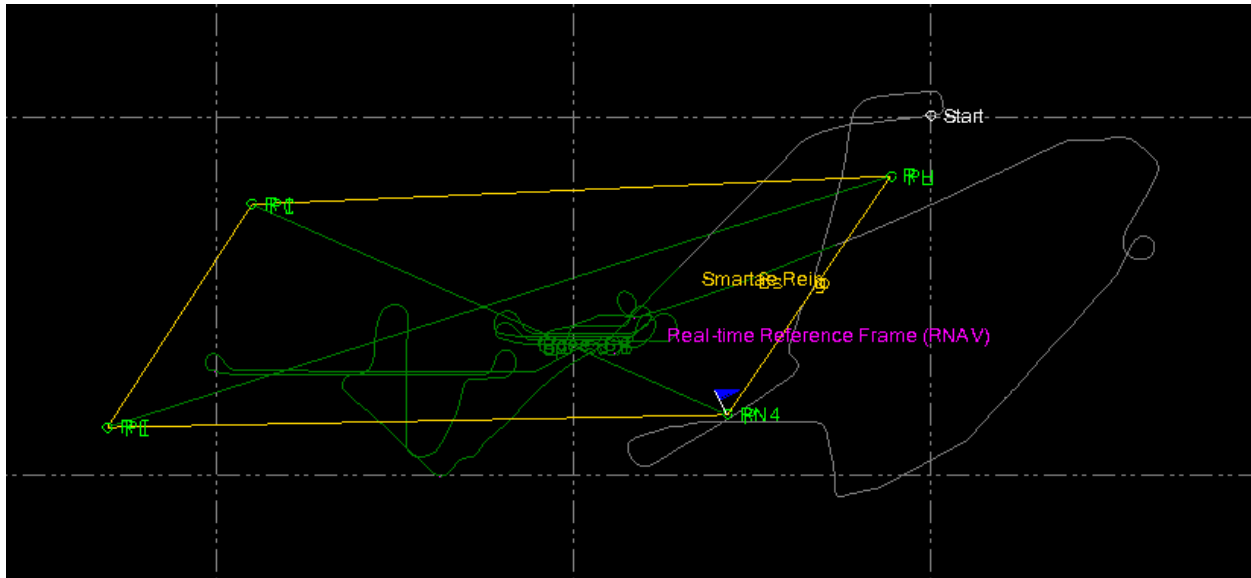
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



RBV18165A



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	-0.037 m	X	0.000 deg
Y	0.007 m	Y	0.000 deg
Z	-0.985 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

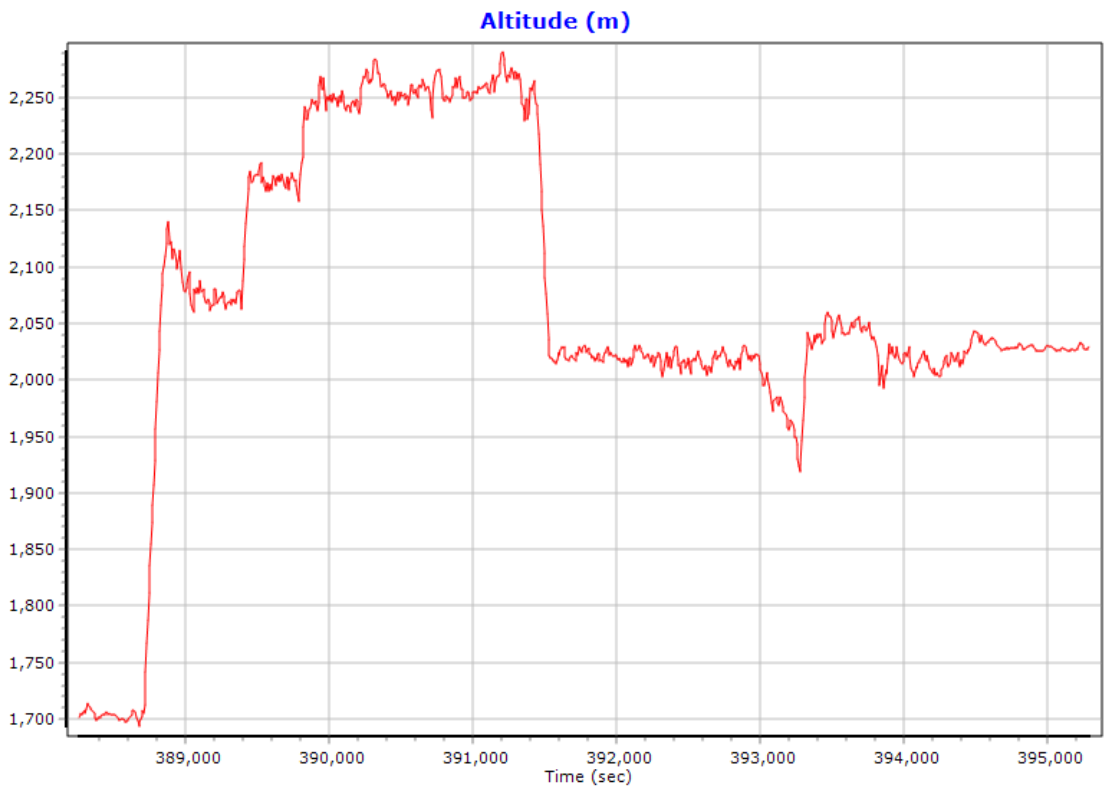
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

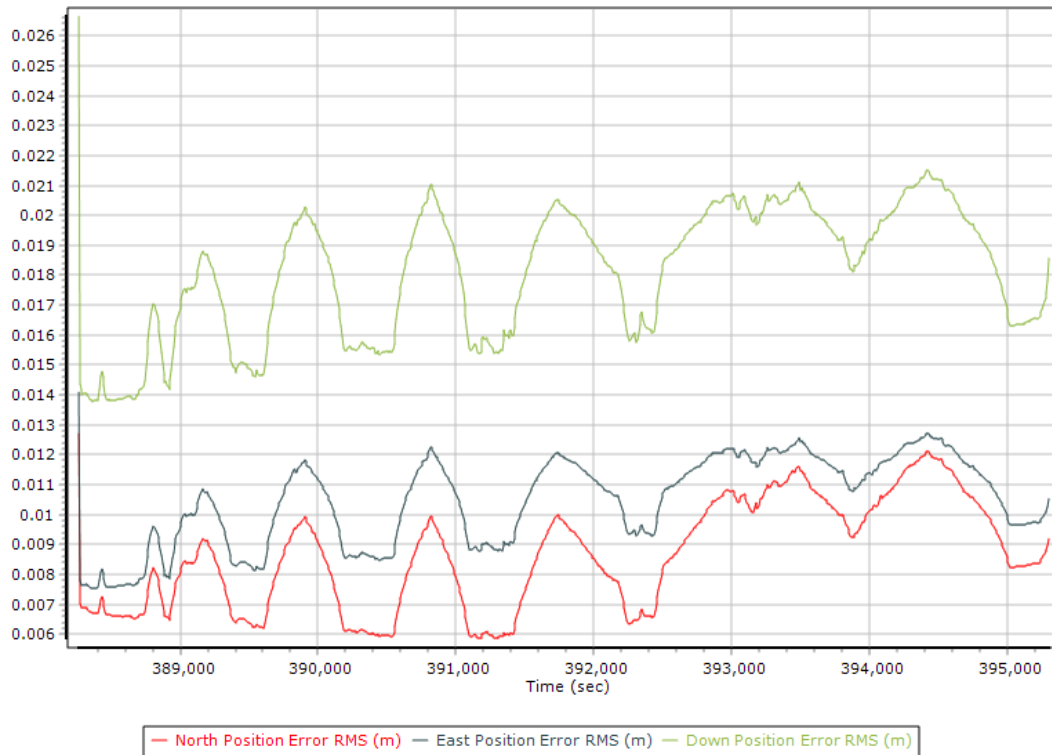
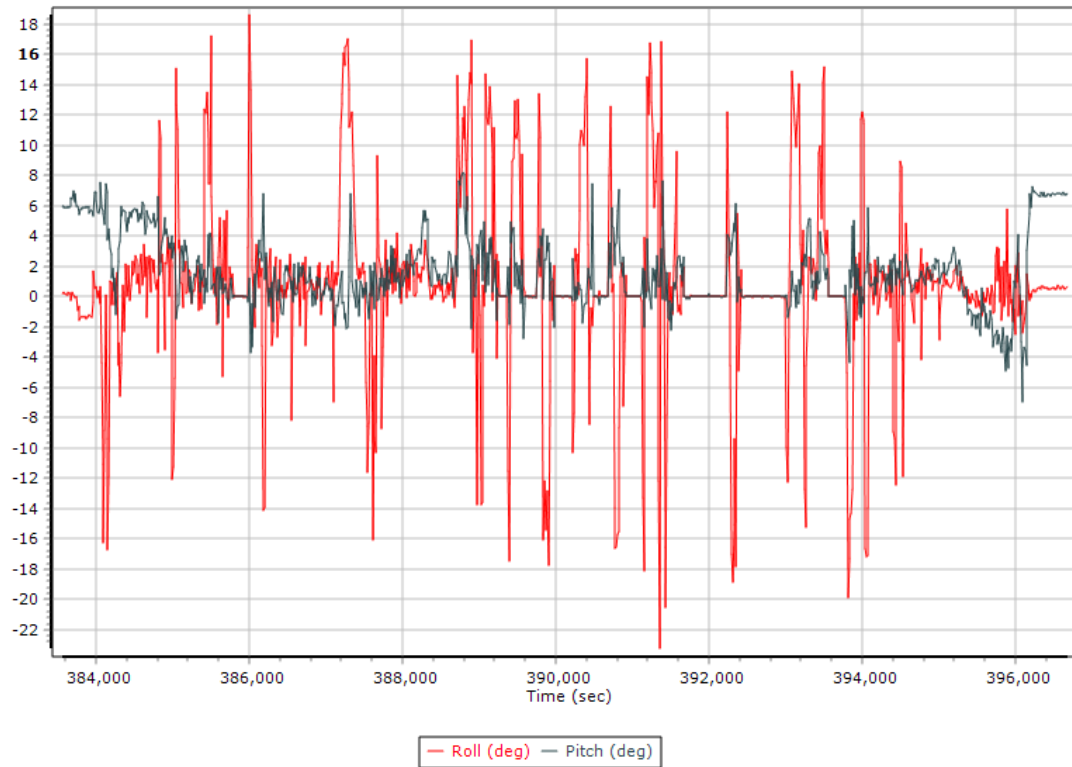
Timing

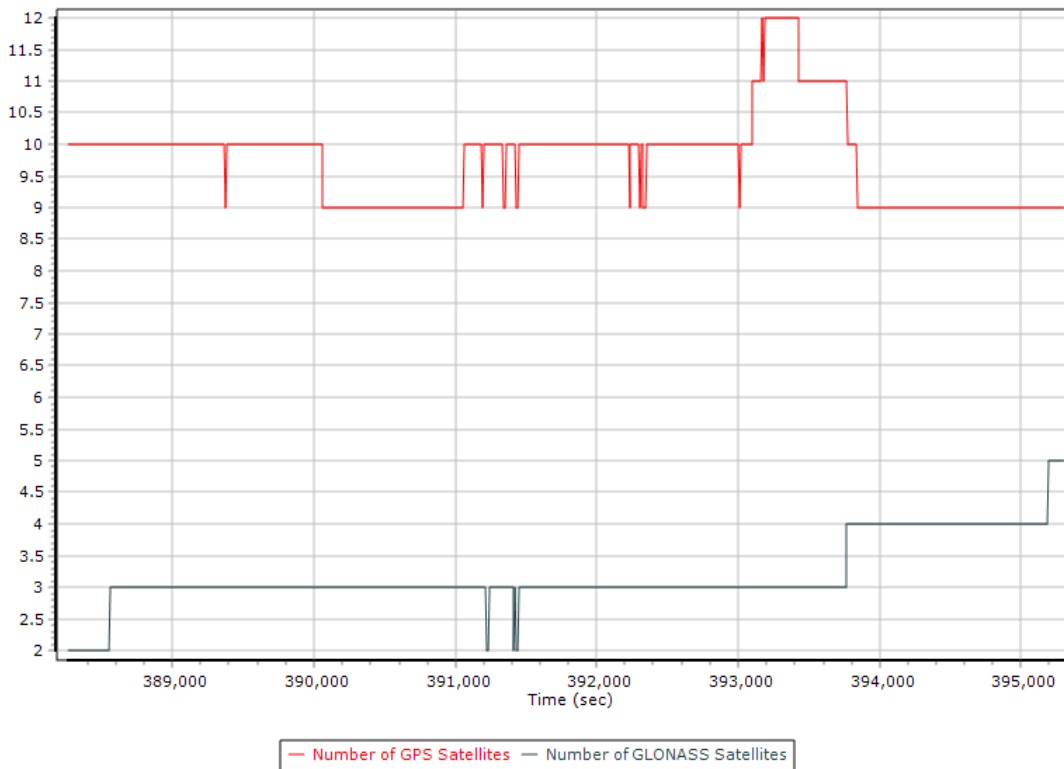
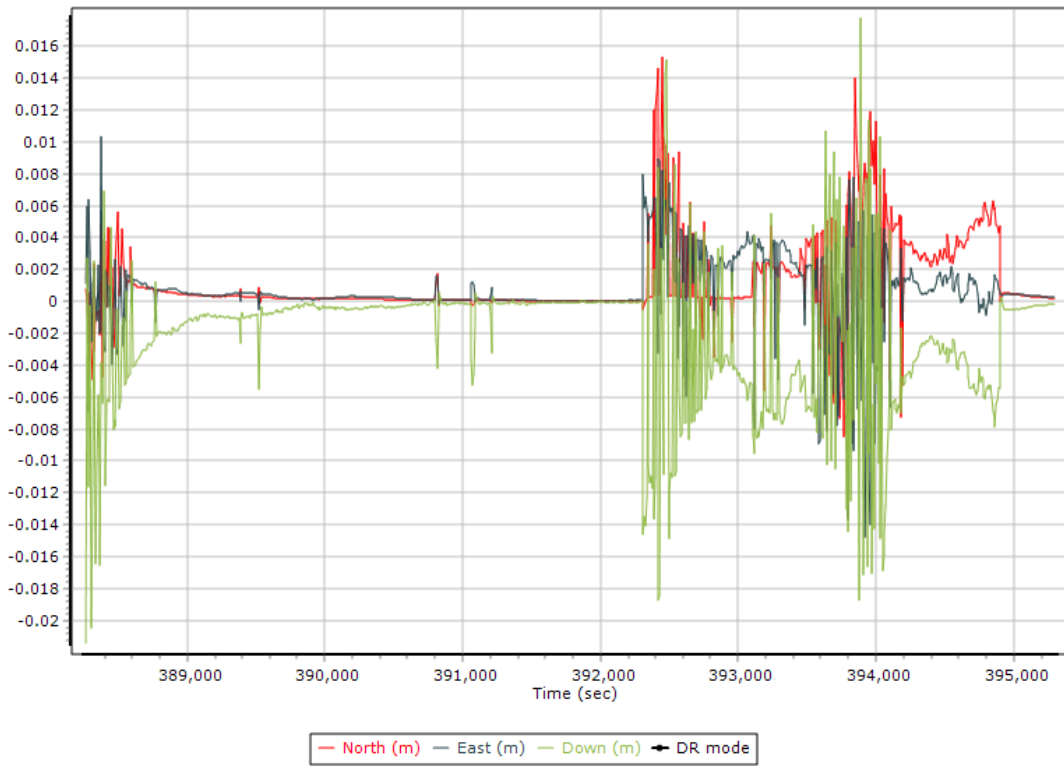
Start: 388260.866
End: 395311.530
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

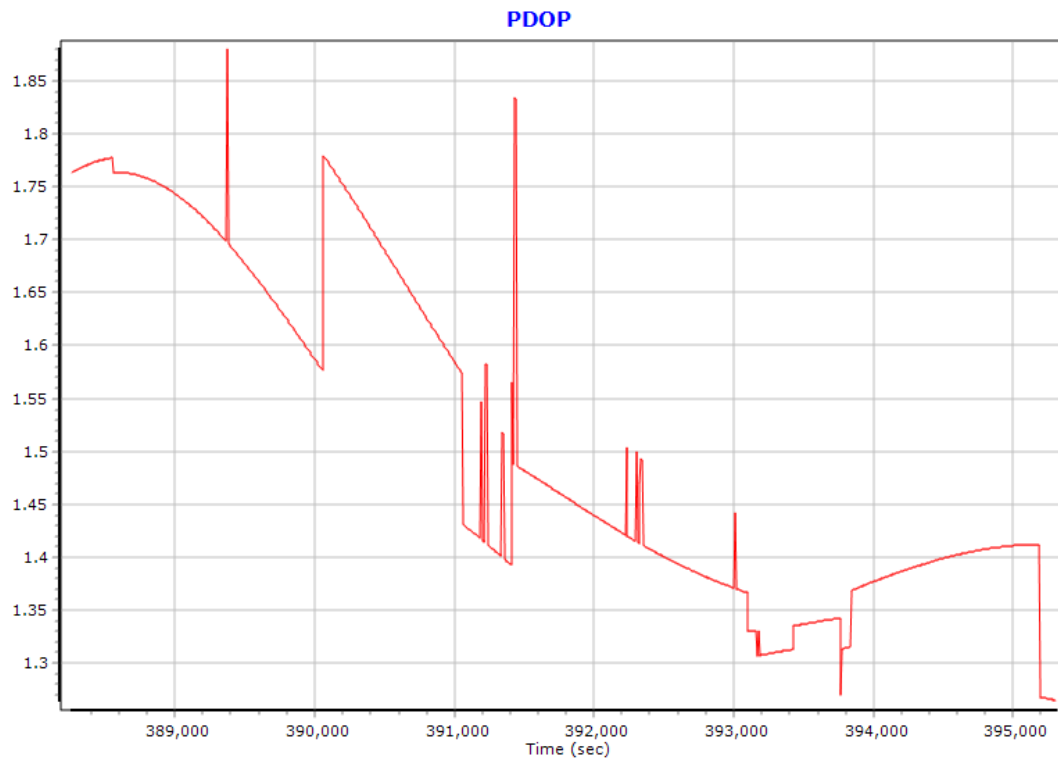
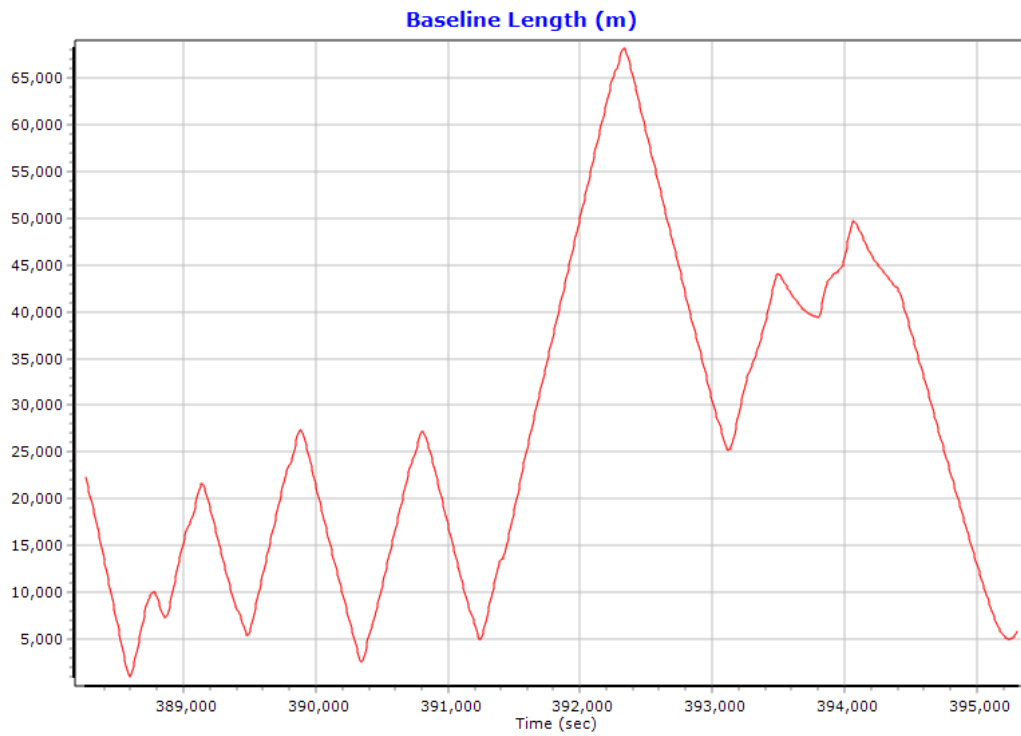
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

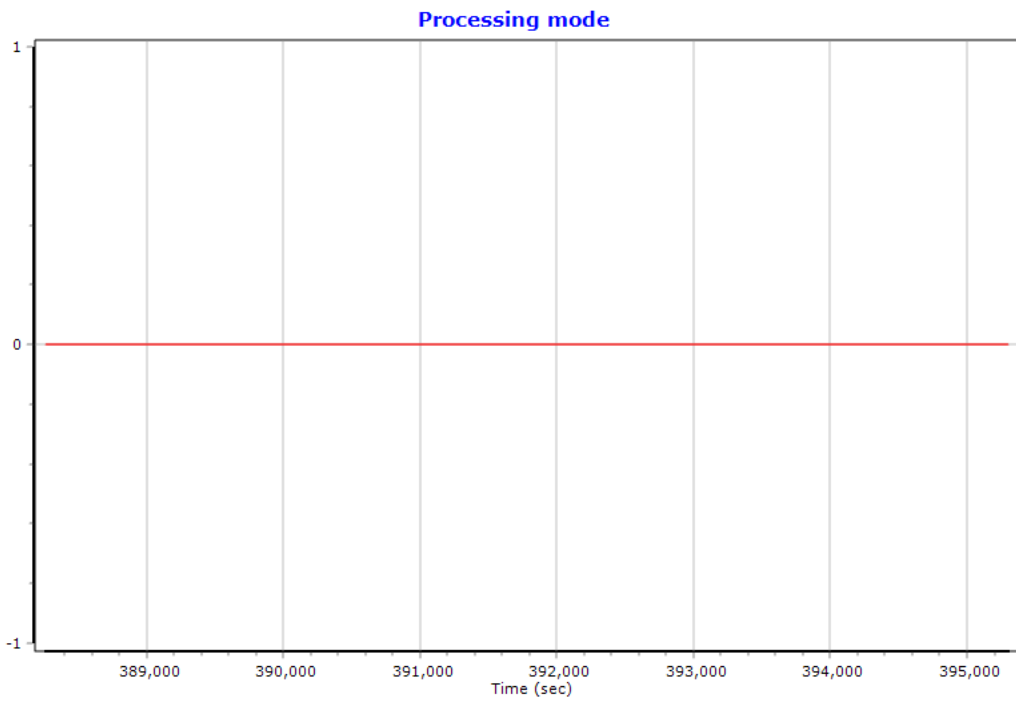
OK Cancel





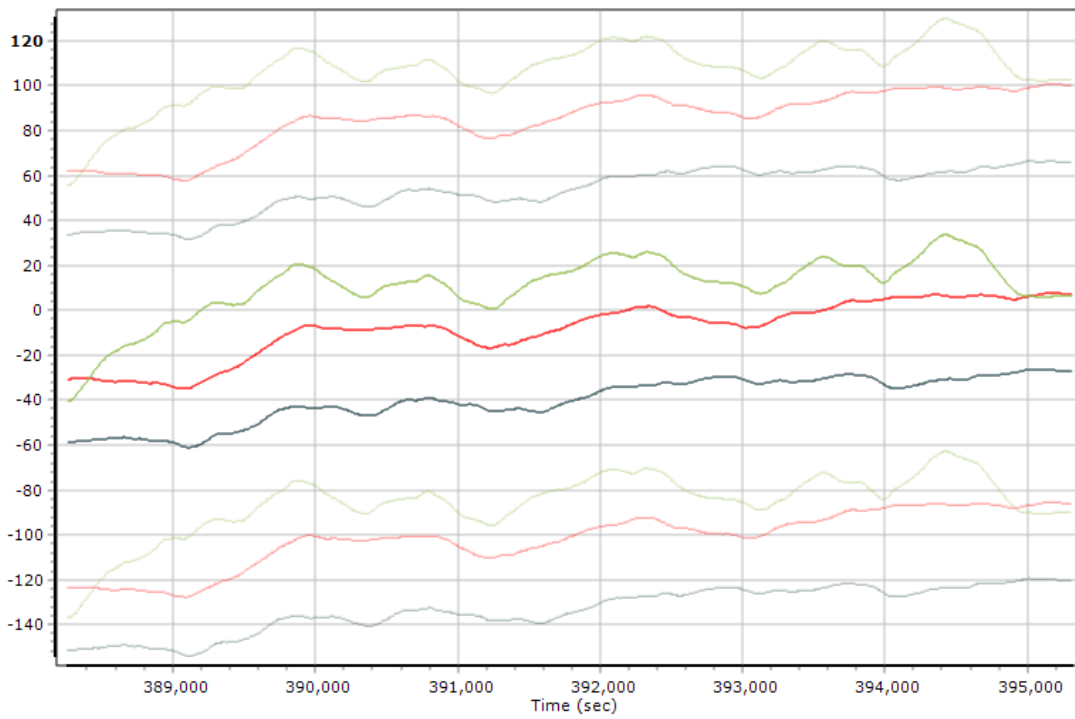




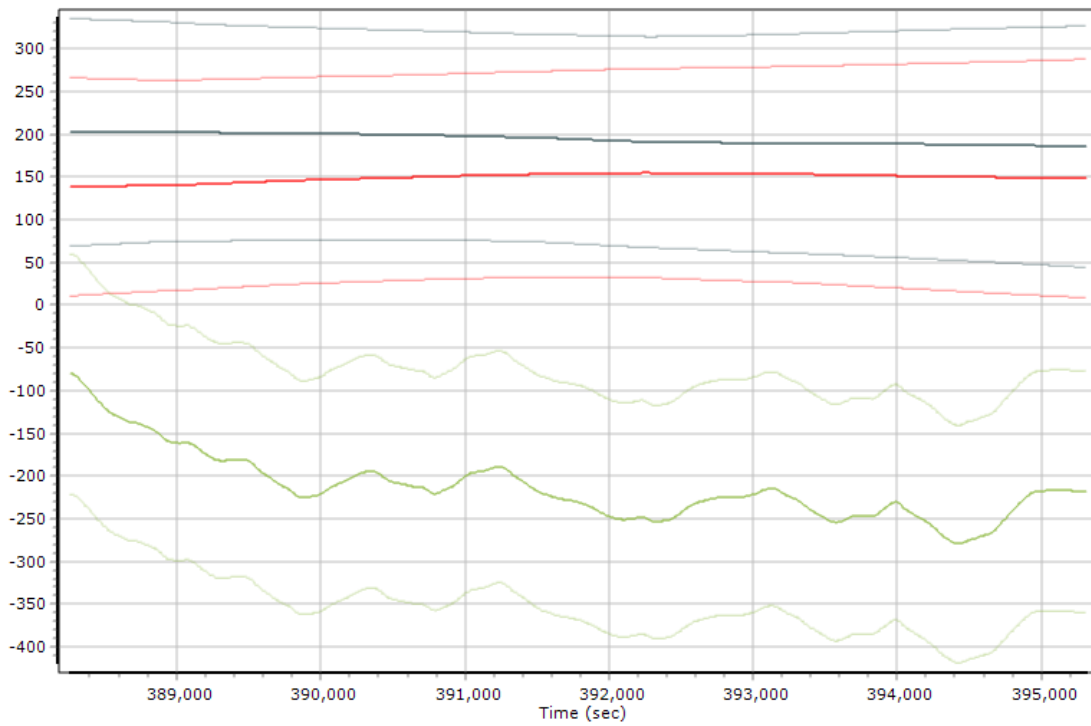


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

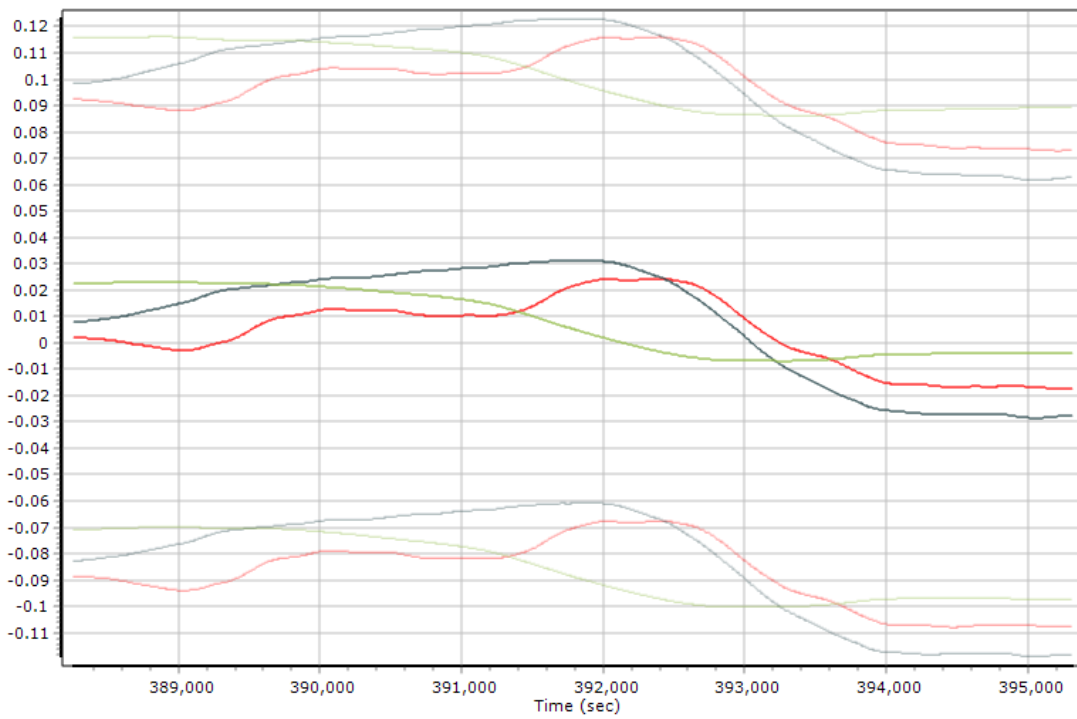
Sensor Errors



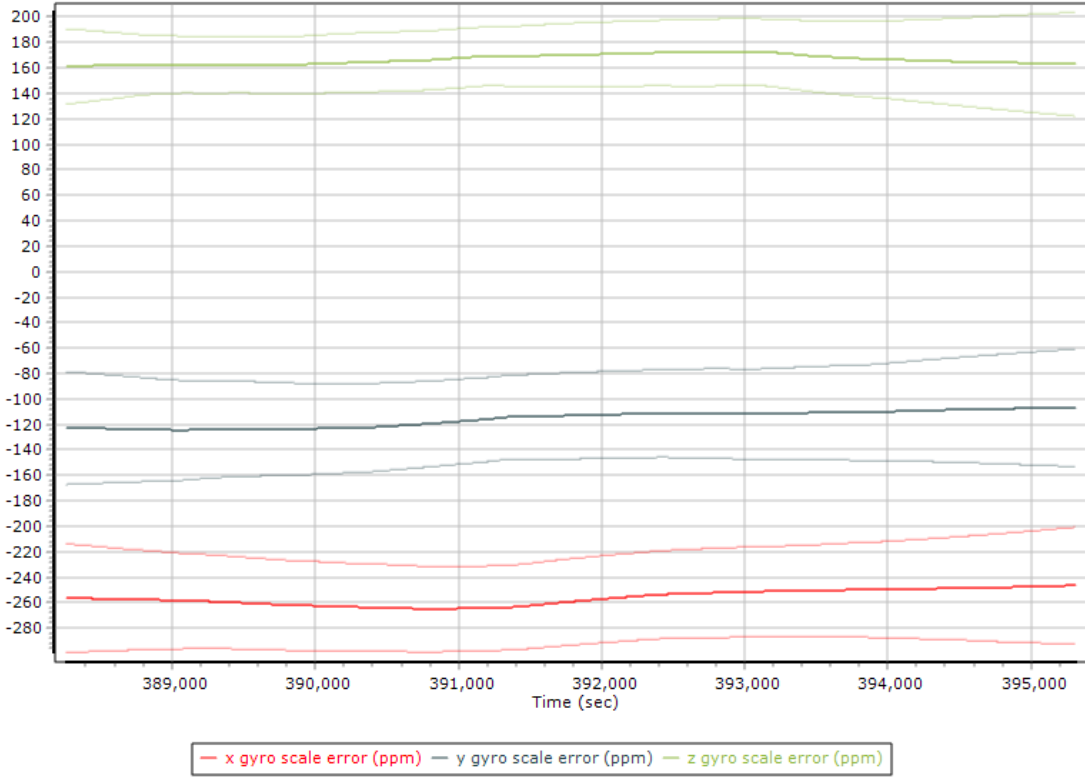
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



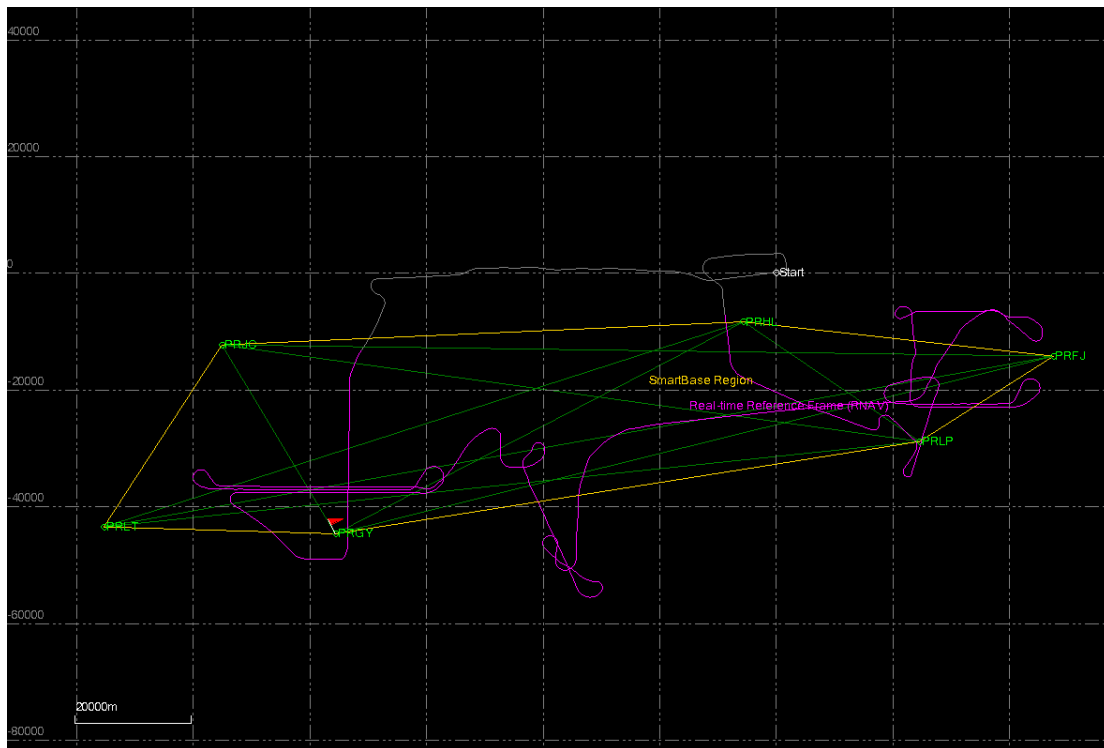
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



RBV18166A



Project Settings

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

Stabilized Mount to IMU Lever Arm

X	-0.034 m
Y	-0.010 m
Z	-0.352 m

Stabilized Mount to IMU Mounting Angles

X	0.000 deg
Y	0.000 deg
Z	0.000 deg

Stabilized Mount to Primary GNSS Lever Arm

X	-0.037 m
Y	0.007 m
Z	-0.985 m

Aircraft to Stabilized Mount Mounting Angles

X	0.000 deg
Y	0.000 deg
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

Timing

Start: 470814.469

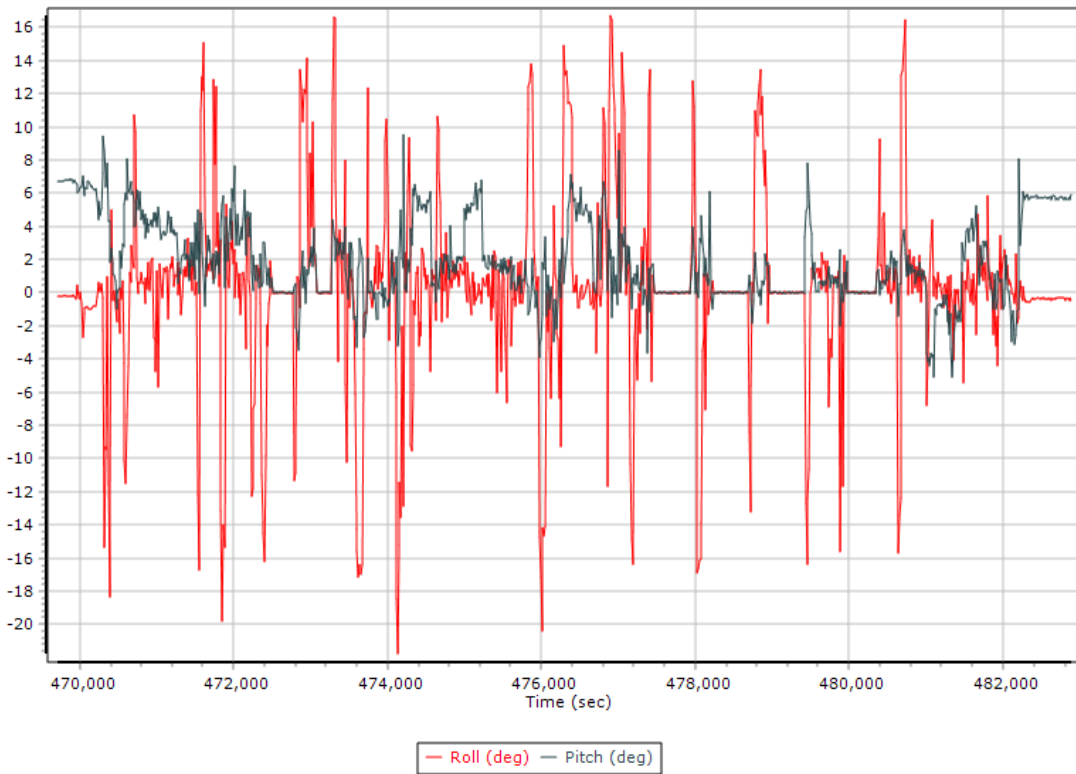
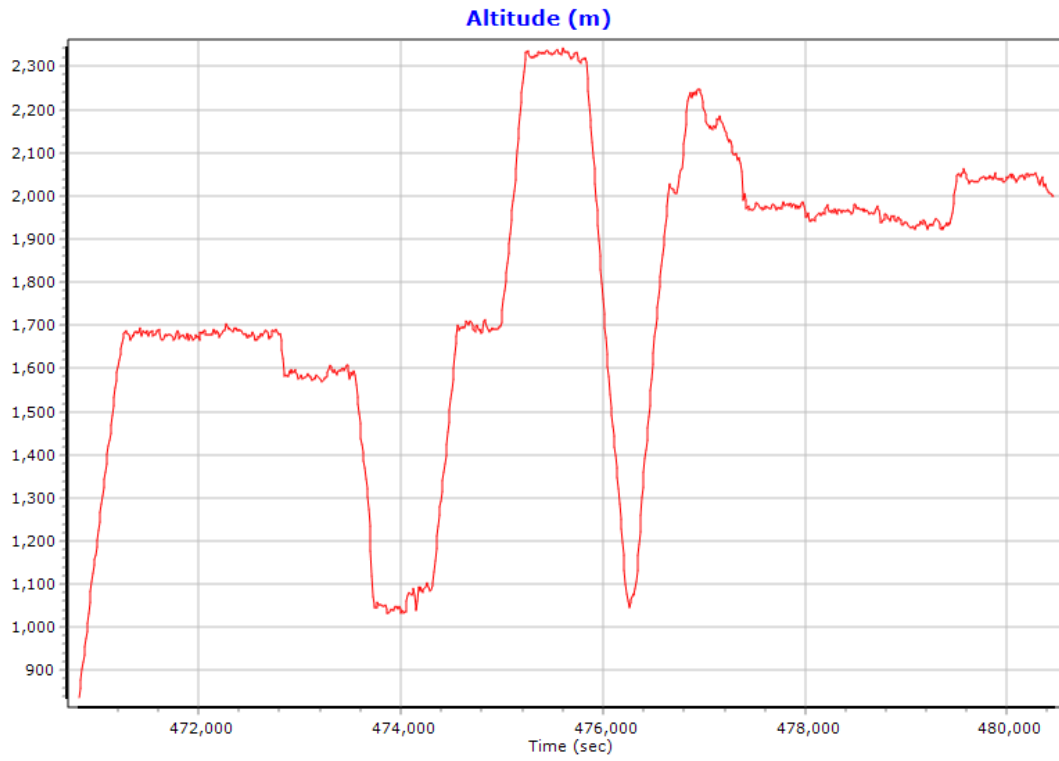
End: 480473.733

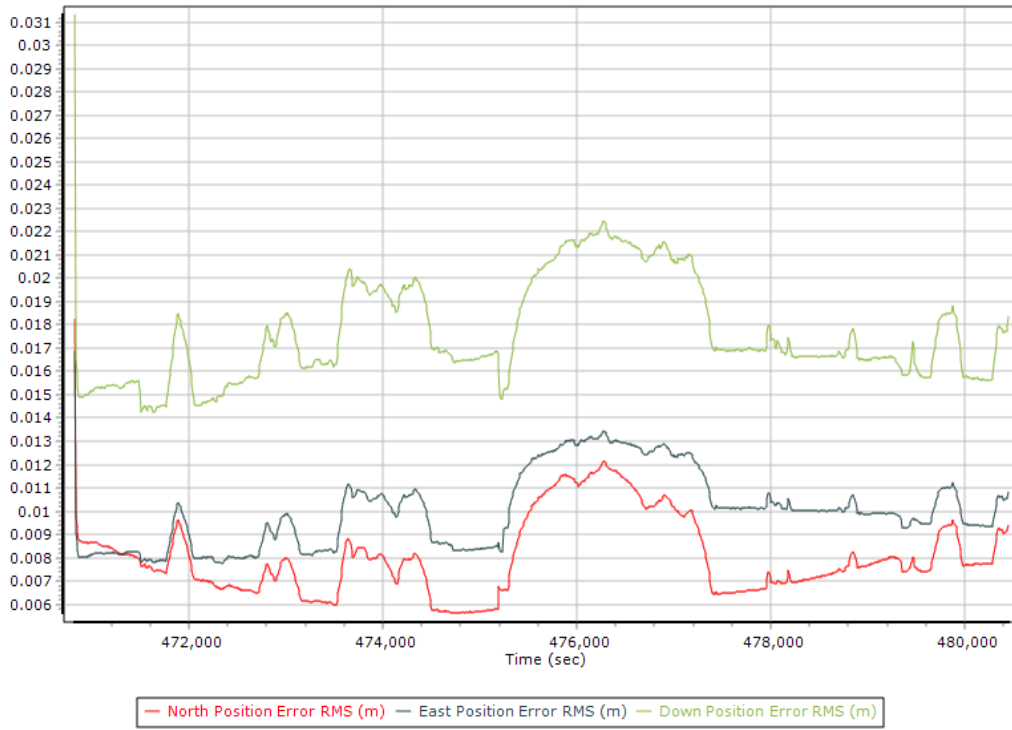
Entire time interval

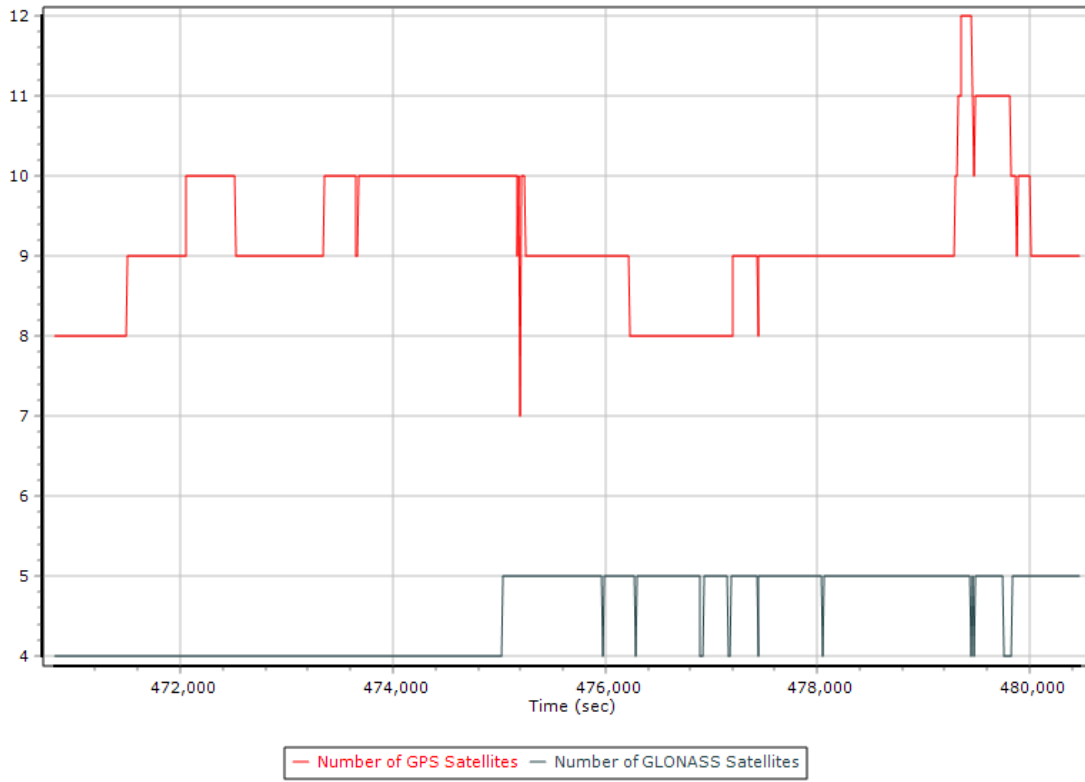
Seconds of start week

UTC Offset: 18.000

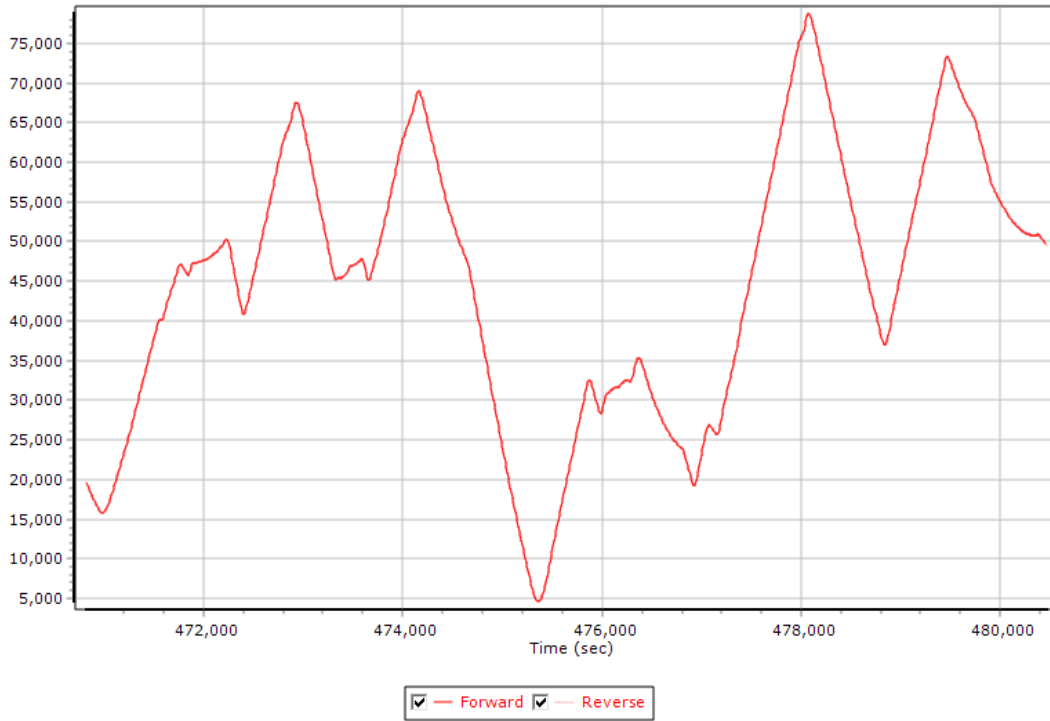
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

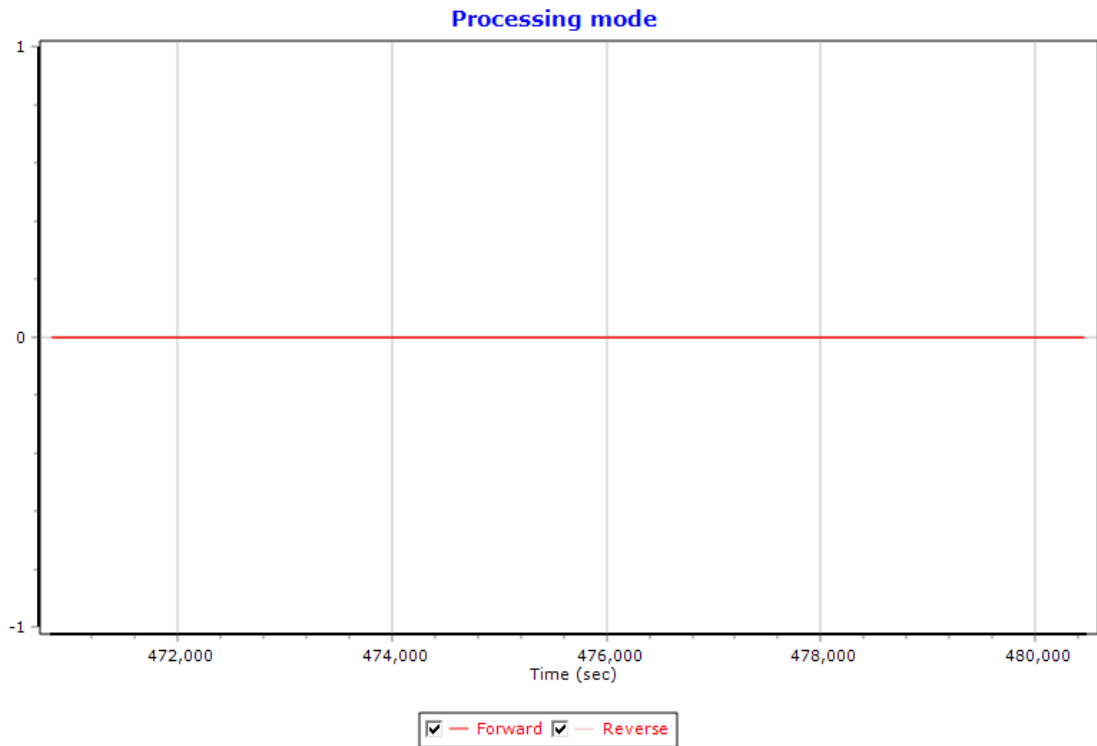
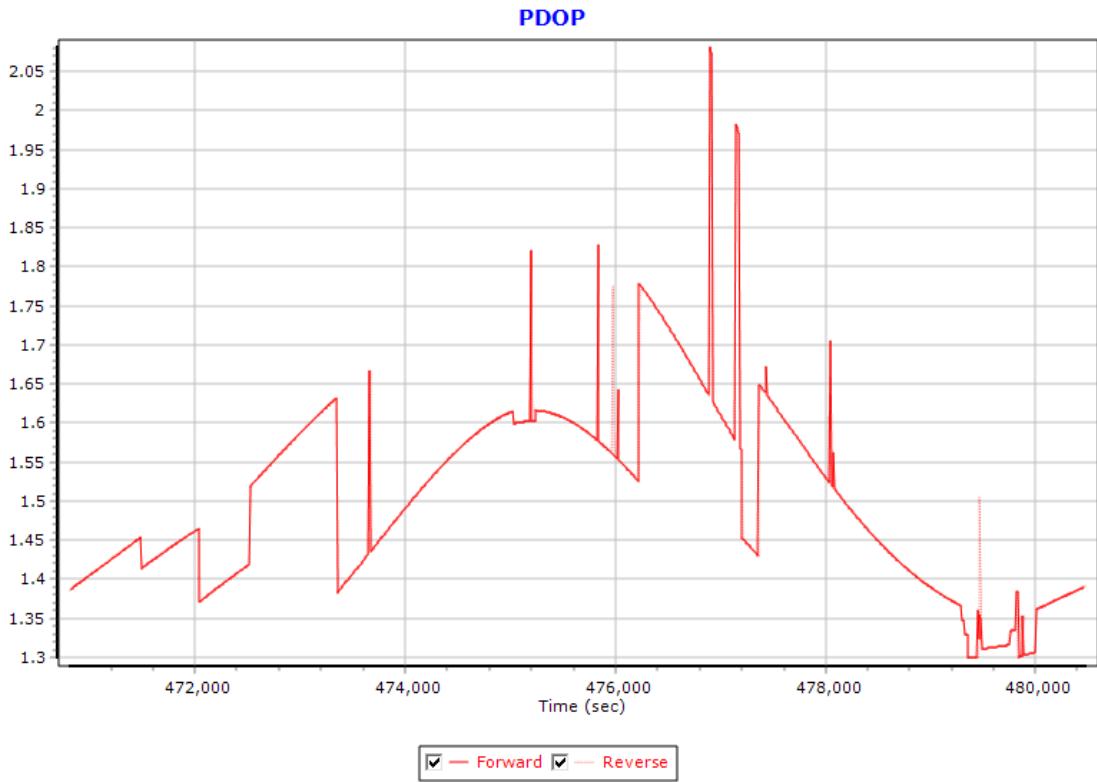






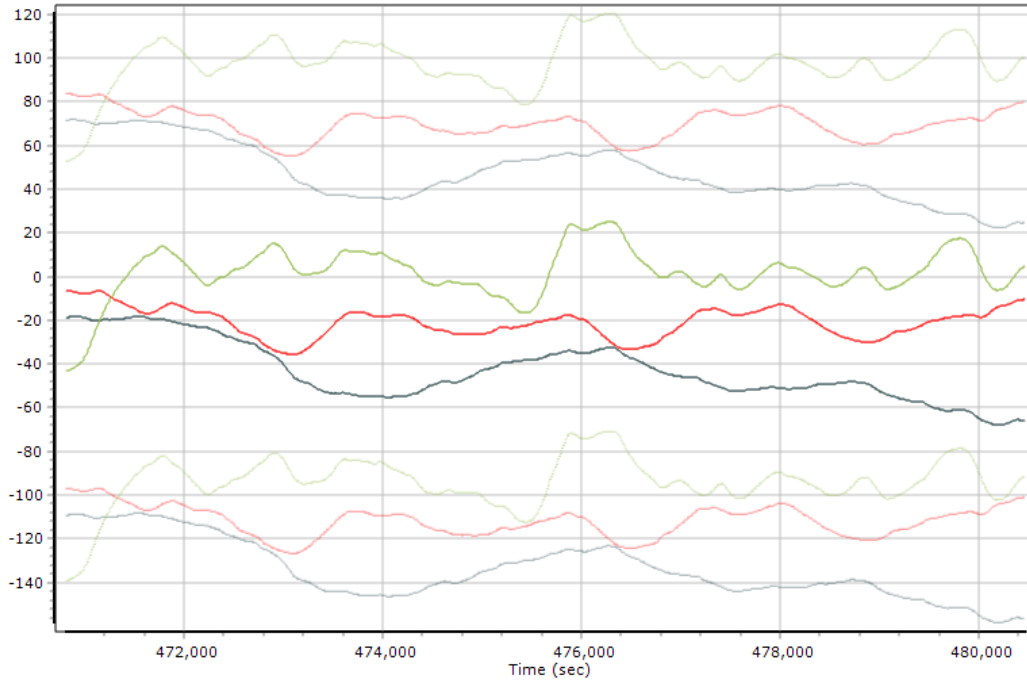
Baseline Length (m)



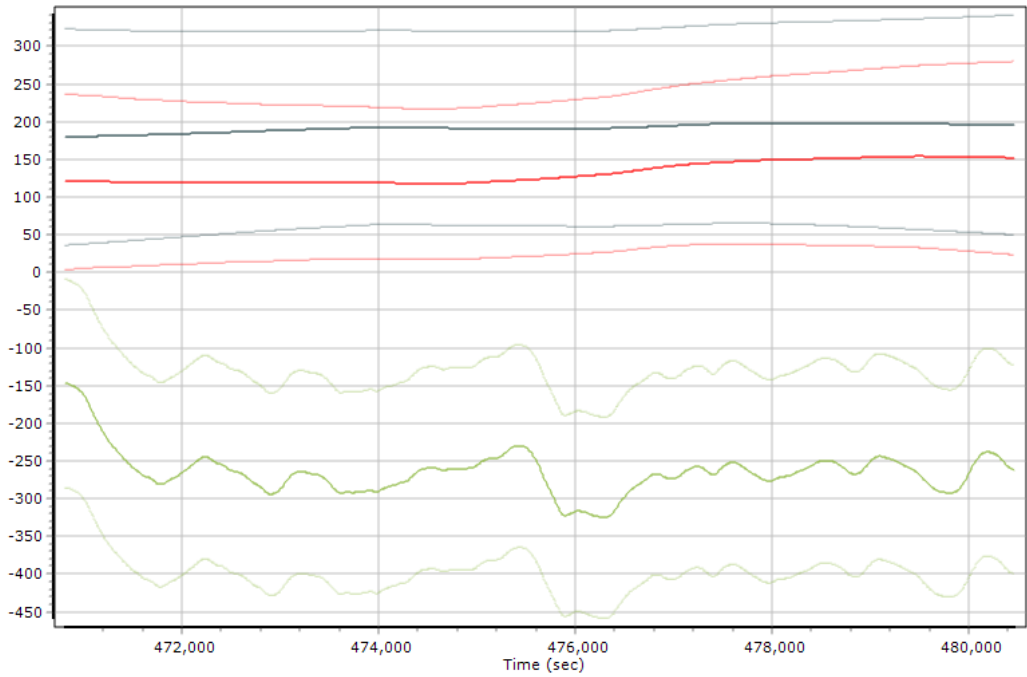


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

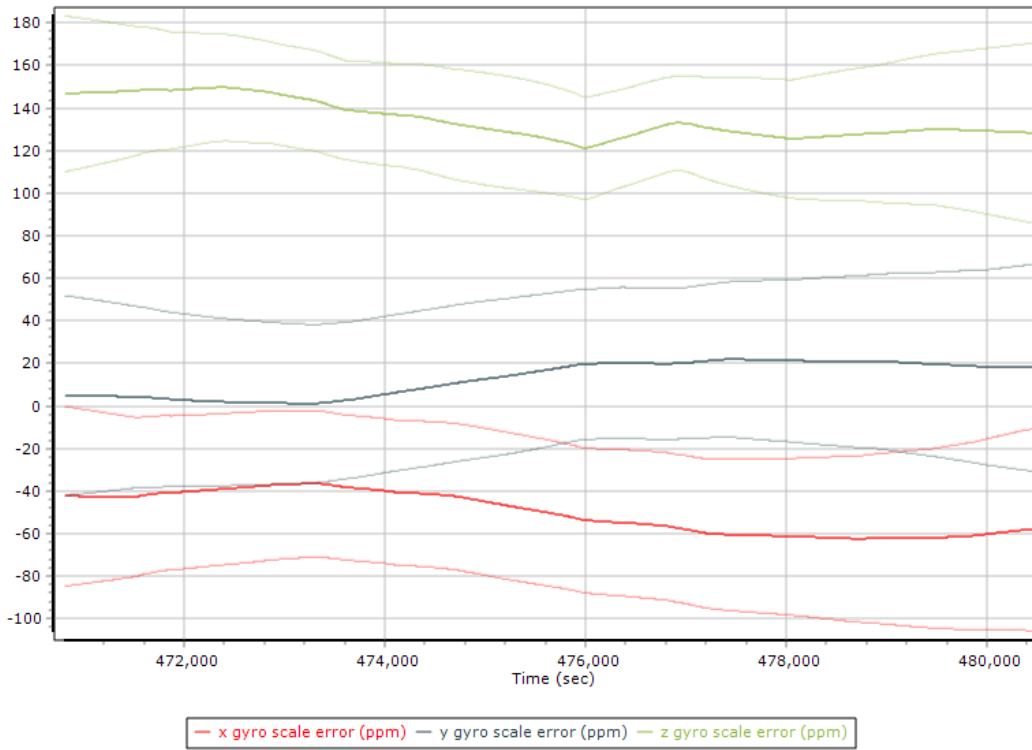
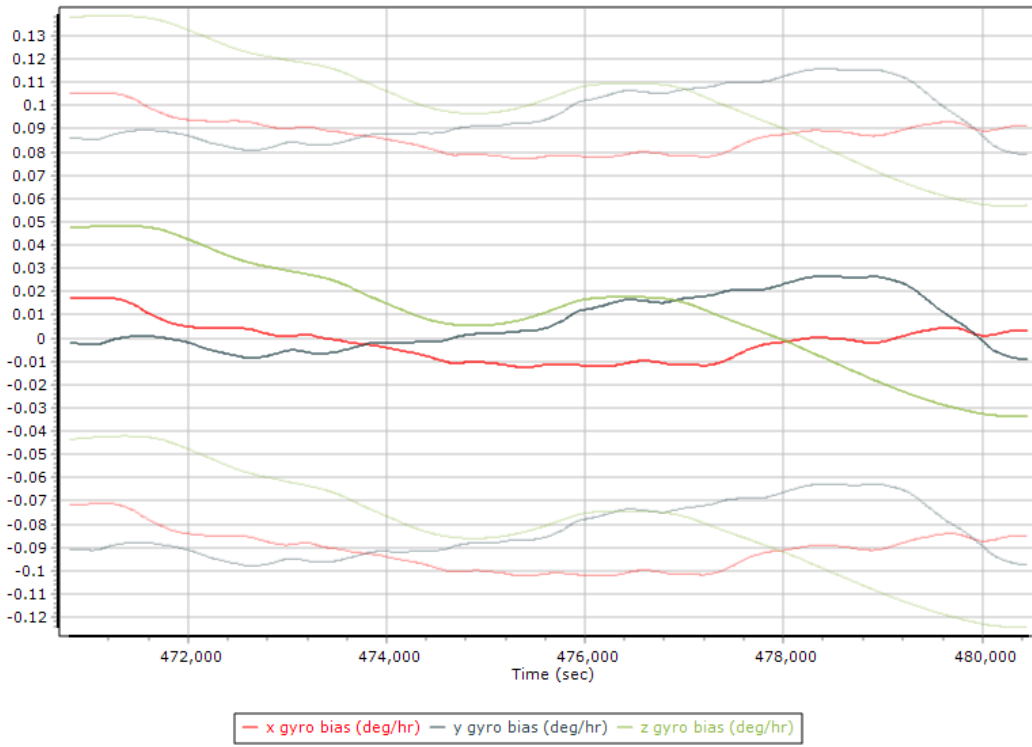
Sensor Errors



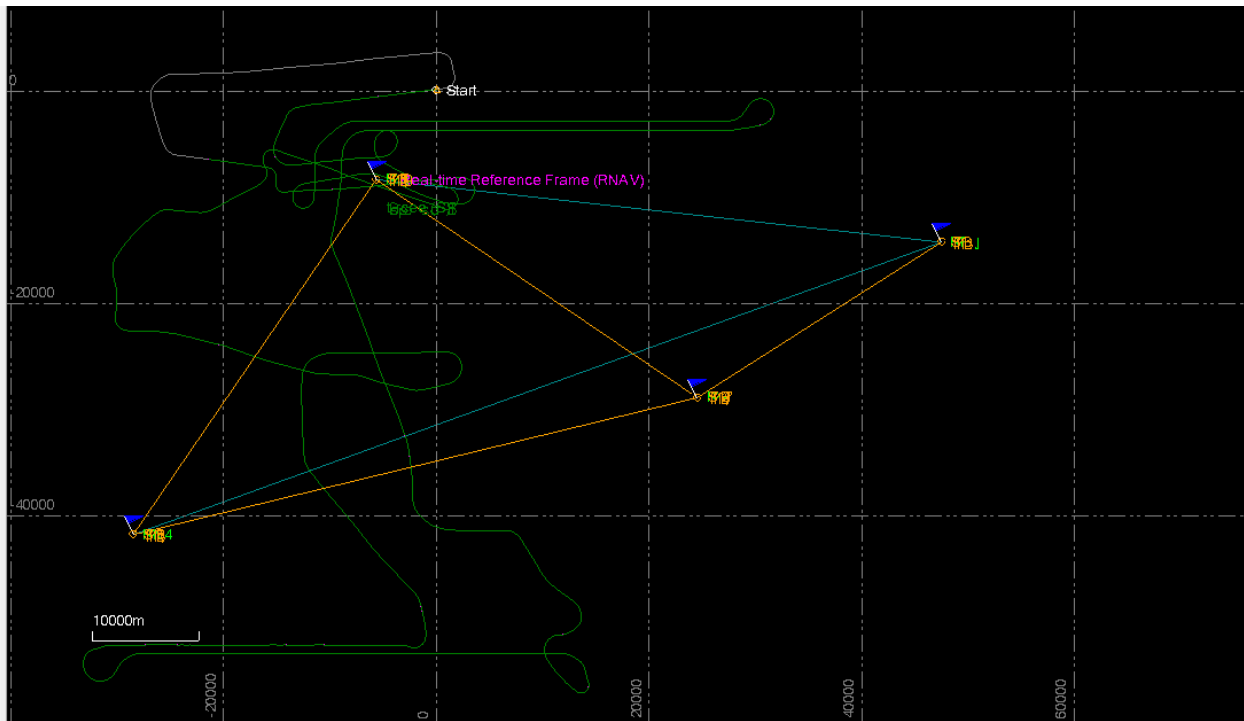
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



RBV18166B



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: -0.037 m	X: 0.000 deg
Y: 0.007 m	Y: 0.000 deg
Z: -0.985 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

Timing

Start

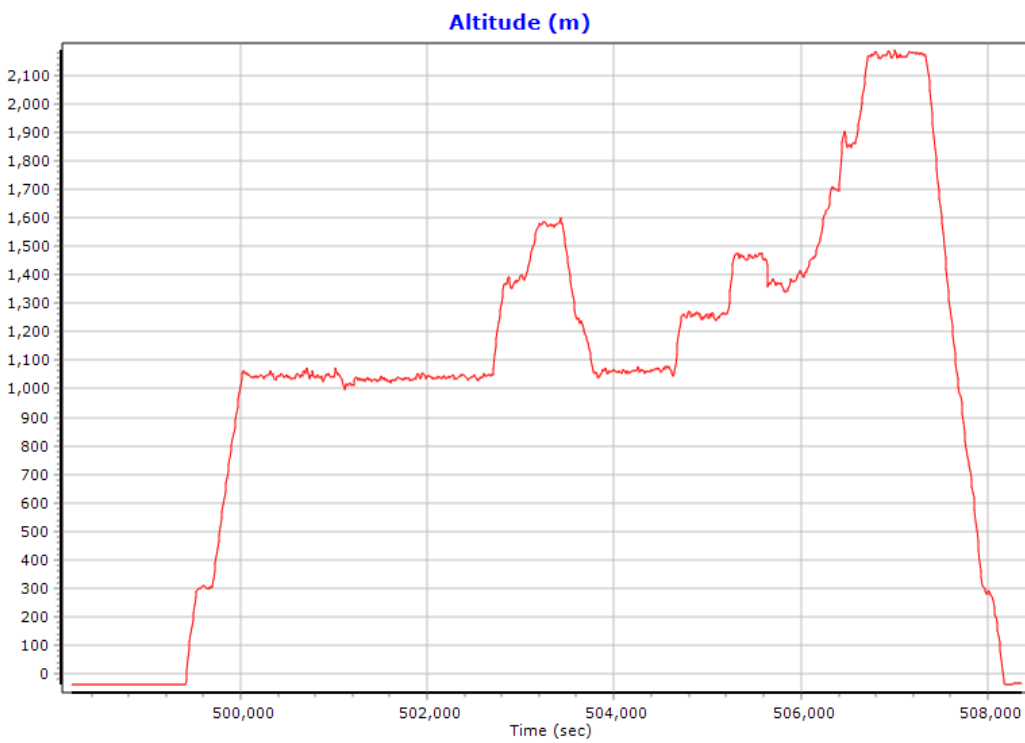
End

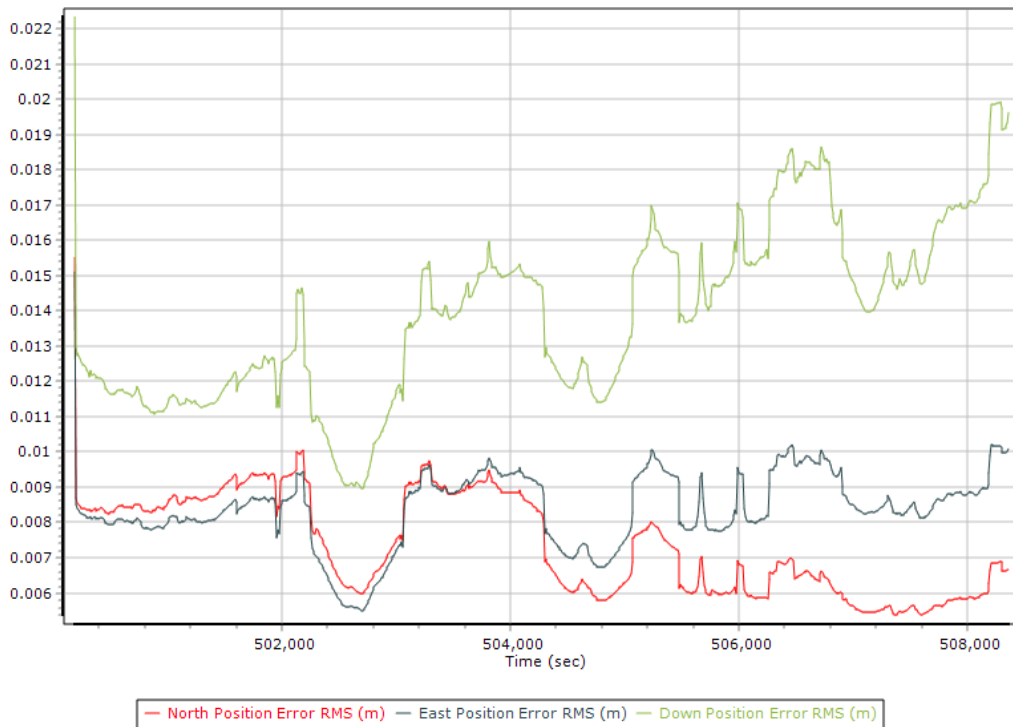
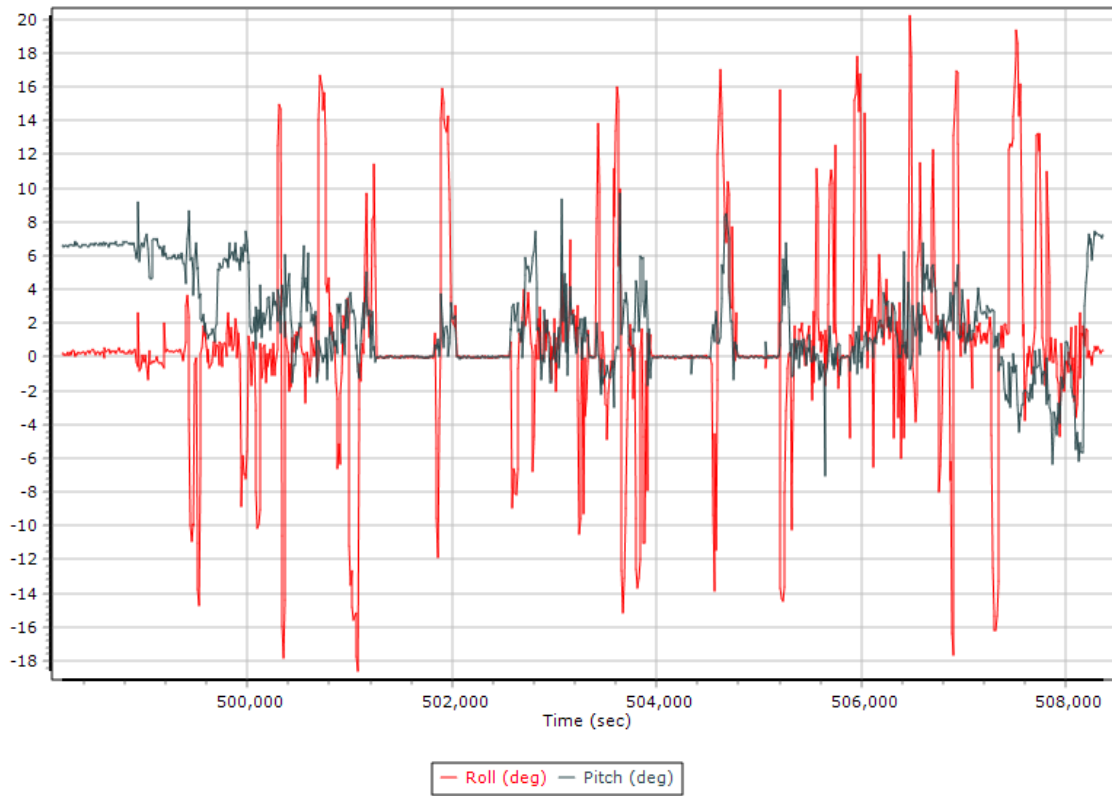
Entire time interval

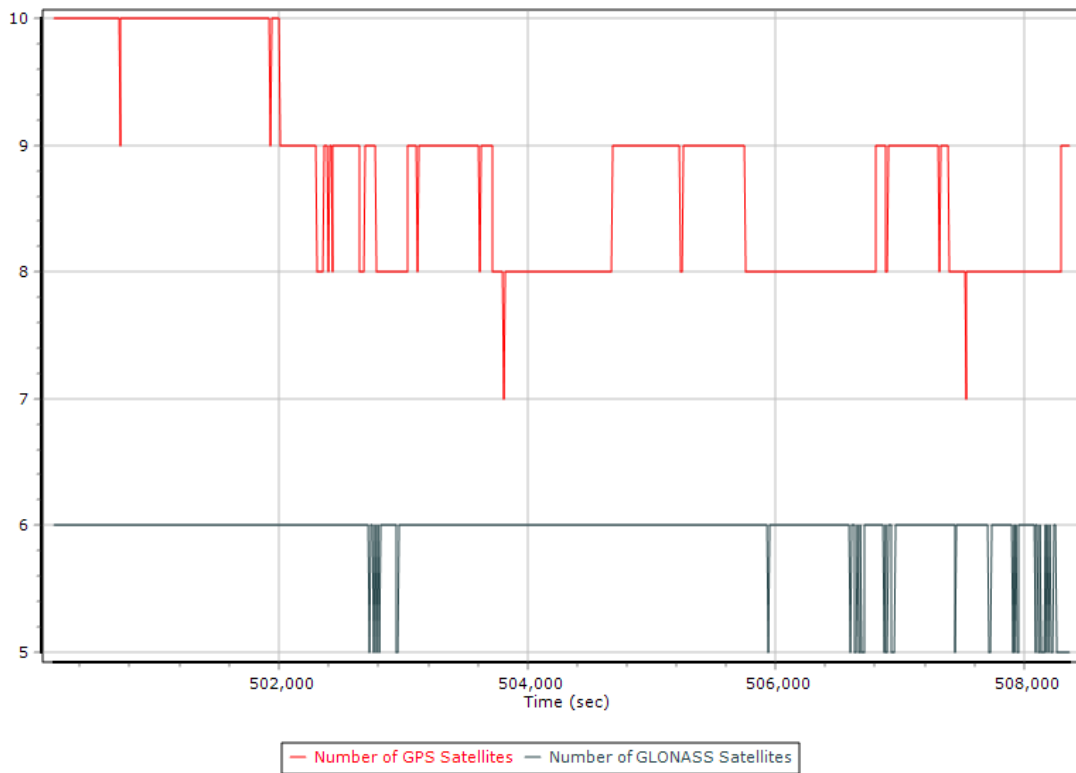
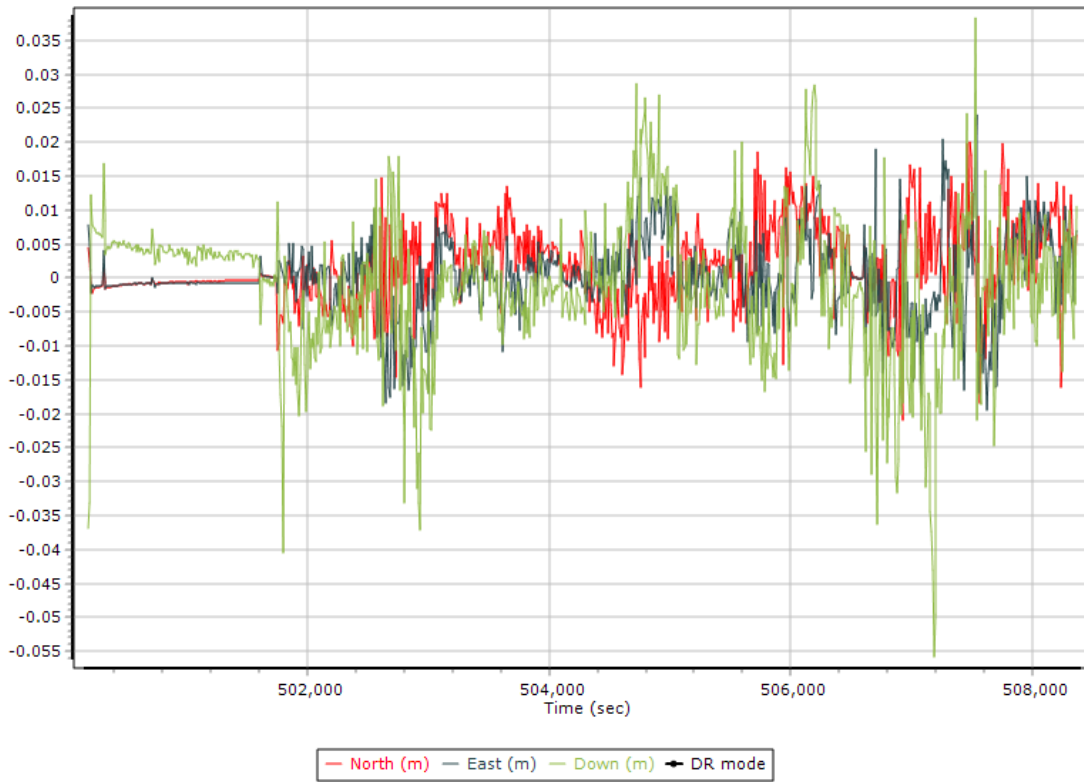
Seconds of start week

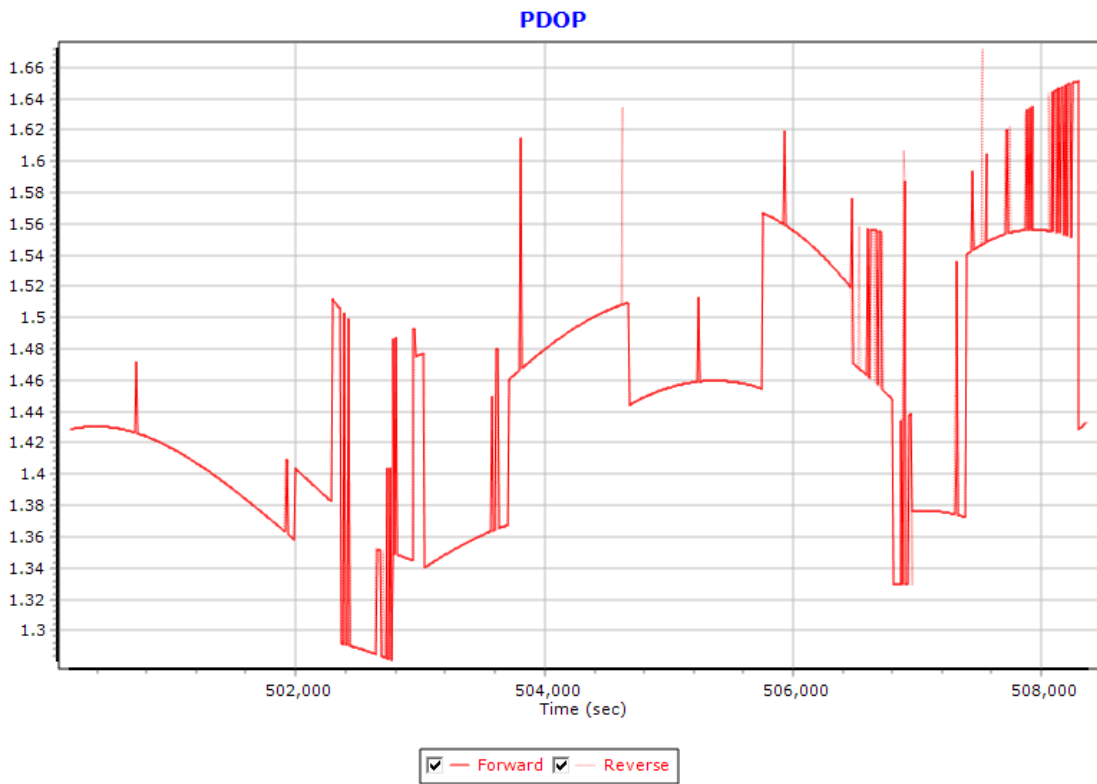
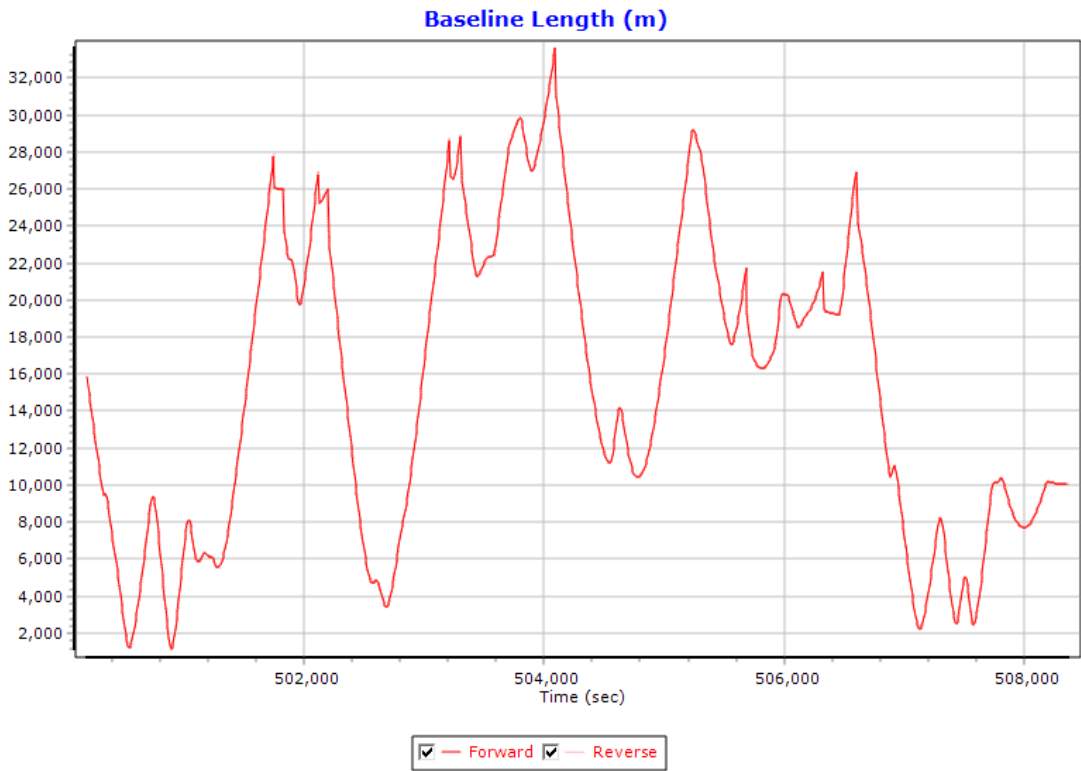
UTC Offset

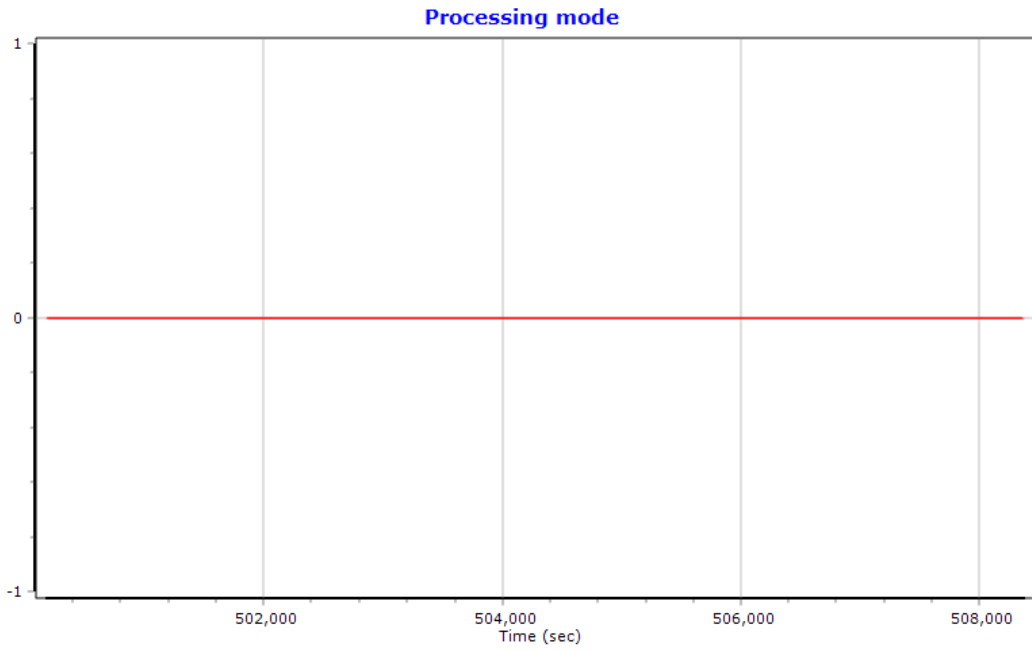
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000







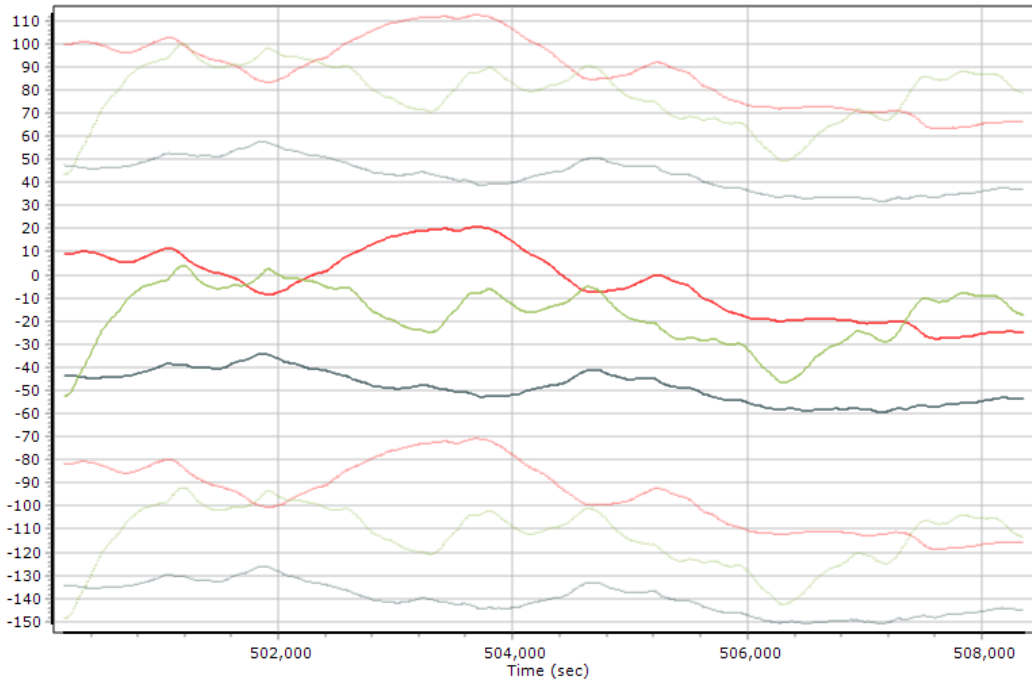




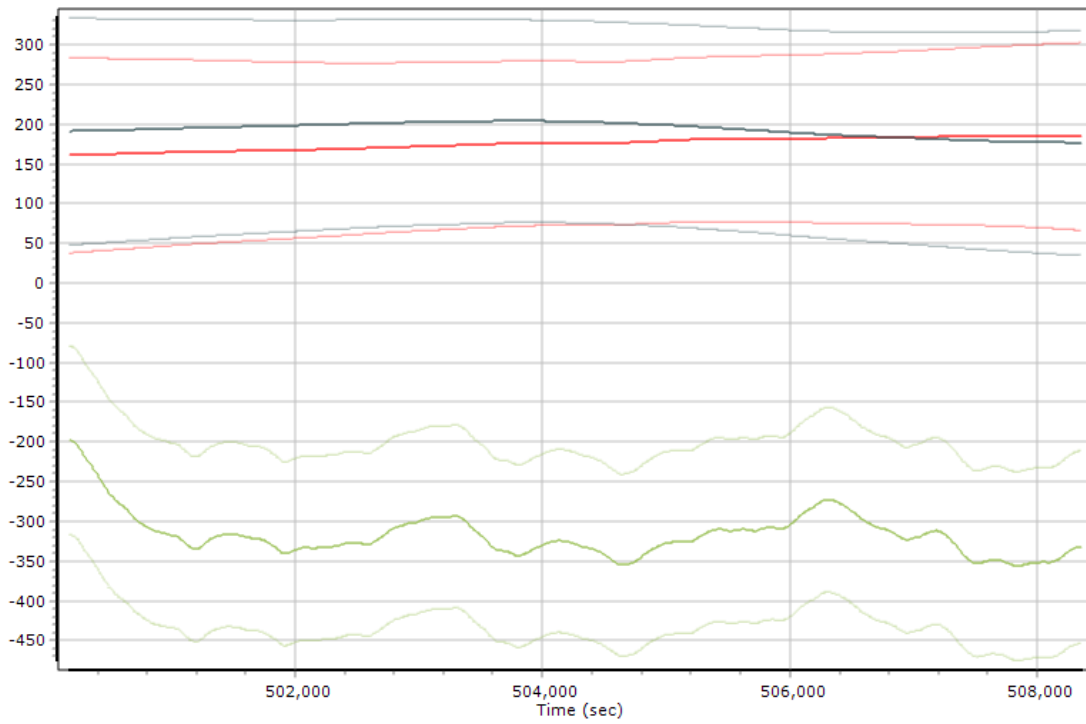
Forward Reverse

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

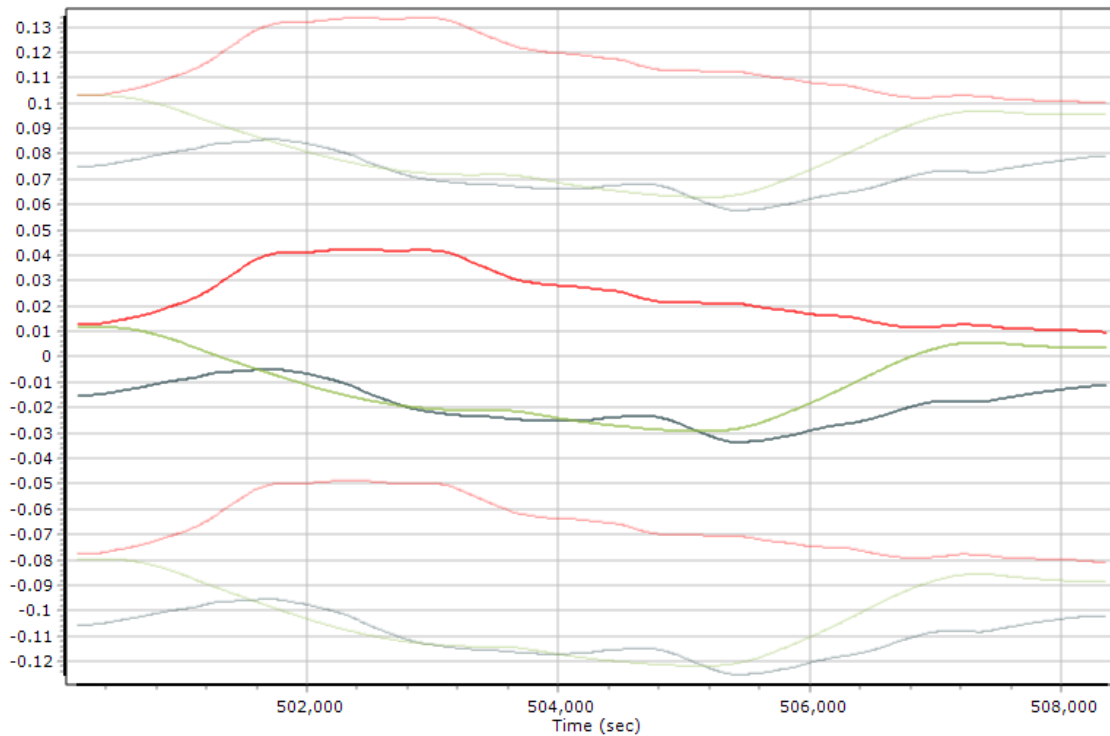
Sensor Errors



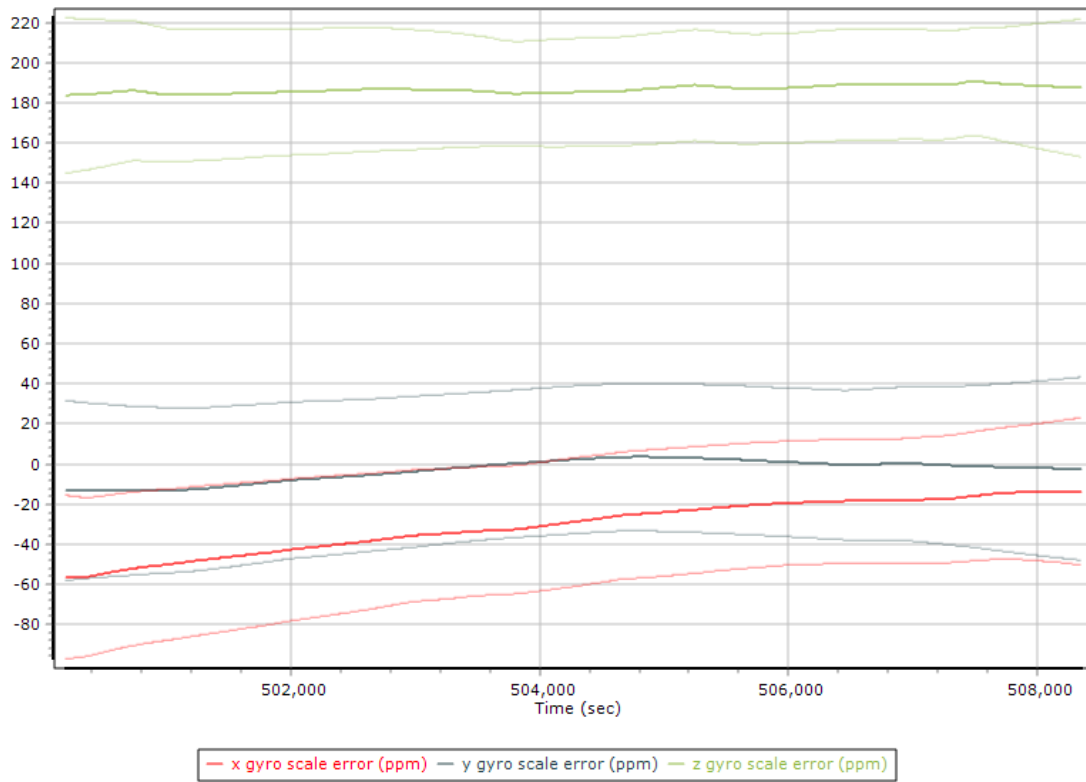
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



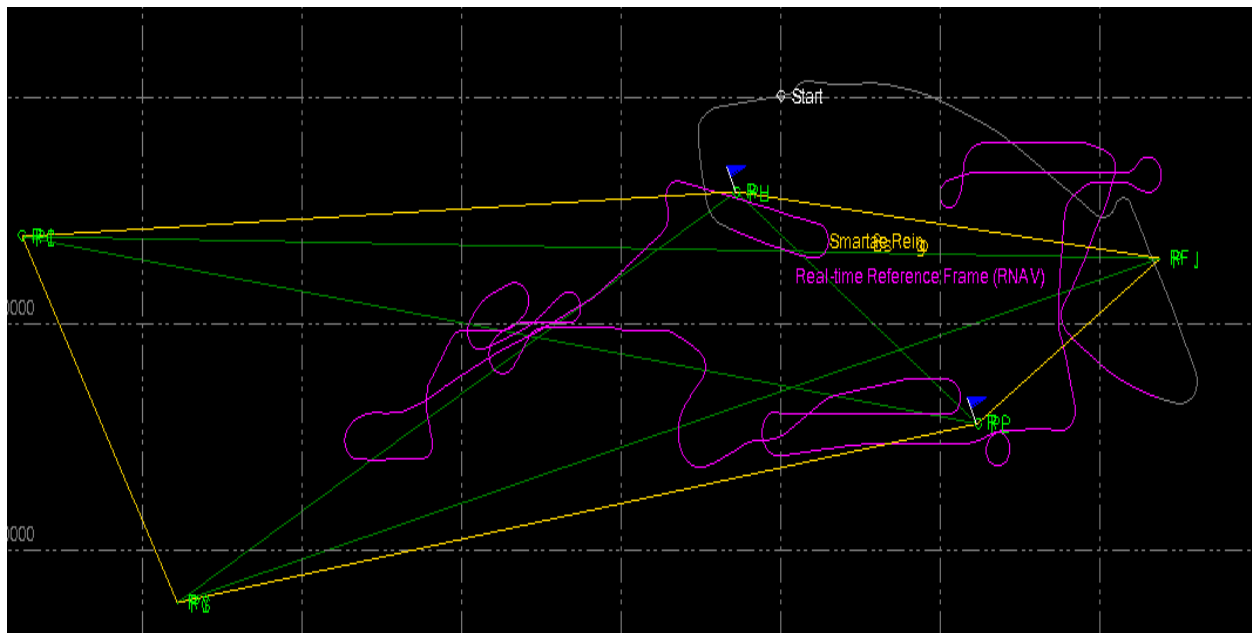
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



RBV18167A



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	-0.034 m
Y	-0.010 m
Z	-0.352 m

Stabilized Mount to IMU Mounting Angles

X	0.000 deg
Y	0.000 deg
Z	0.000 deg

Stabilized Mount to Primary GNSS Lever Arm

X	-0.037 m
Y	0.007 m
Z	-0.985 m

Aircraft to Stabilized Mount Mounting Angles

X	0.000 deg
Y	0.000 deg
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

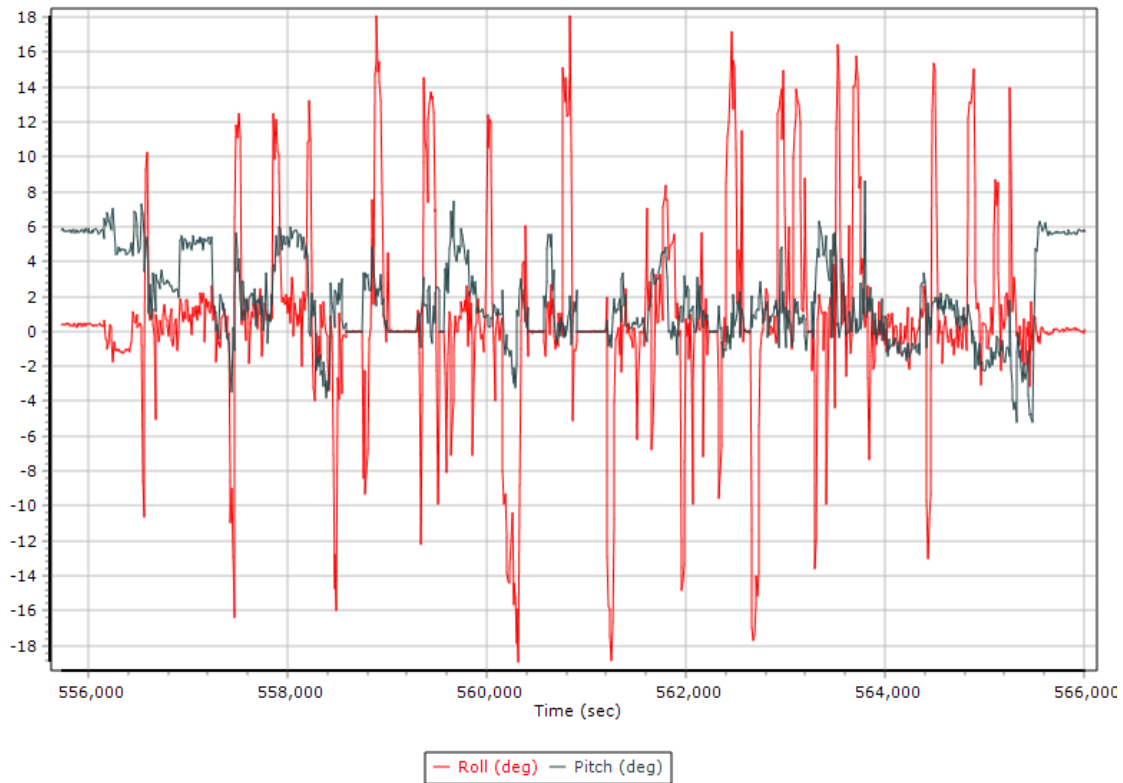
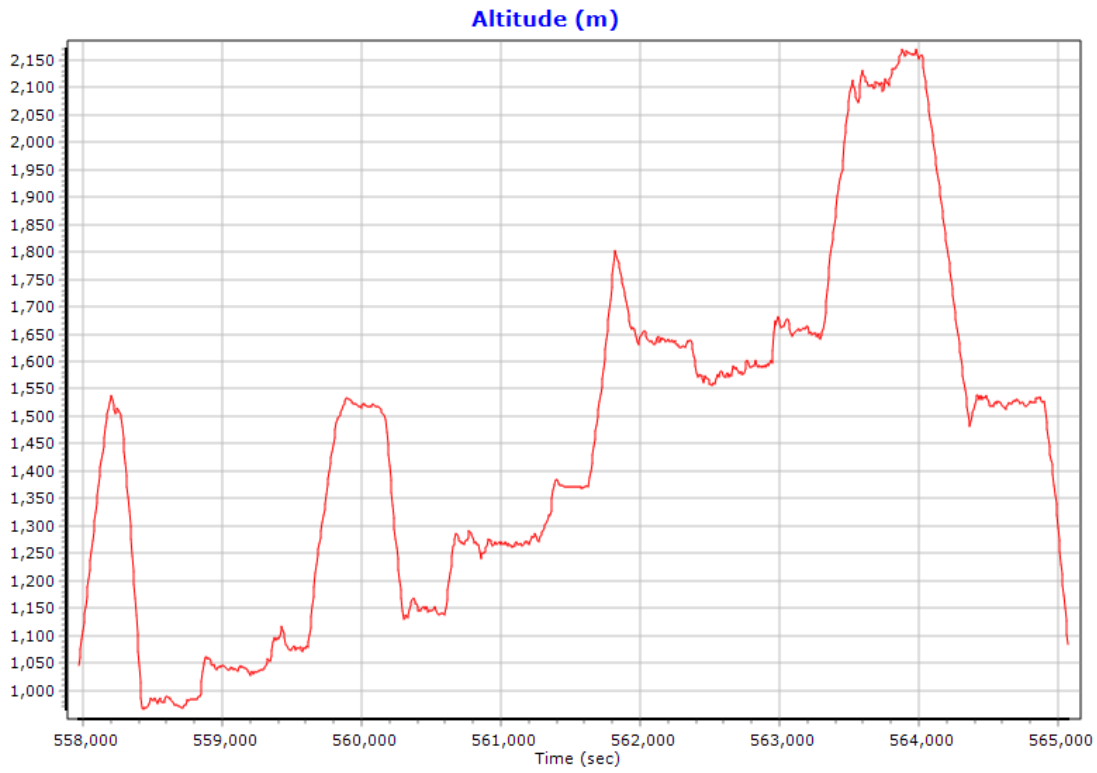
Start: 557966.766
End: 565078.436

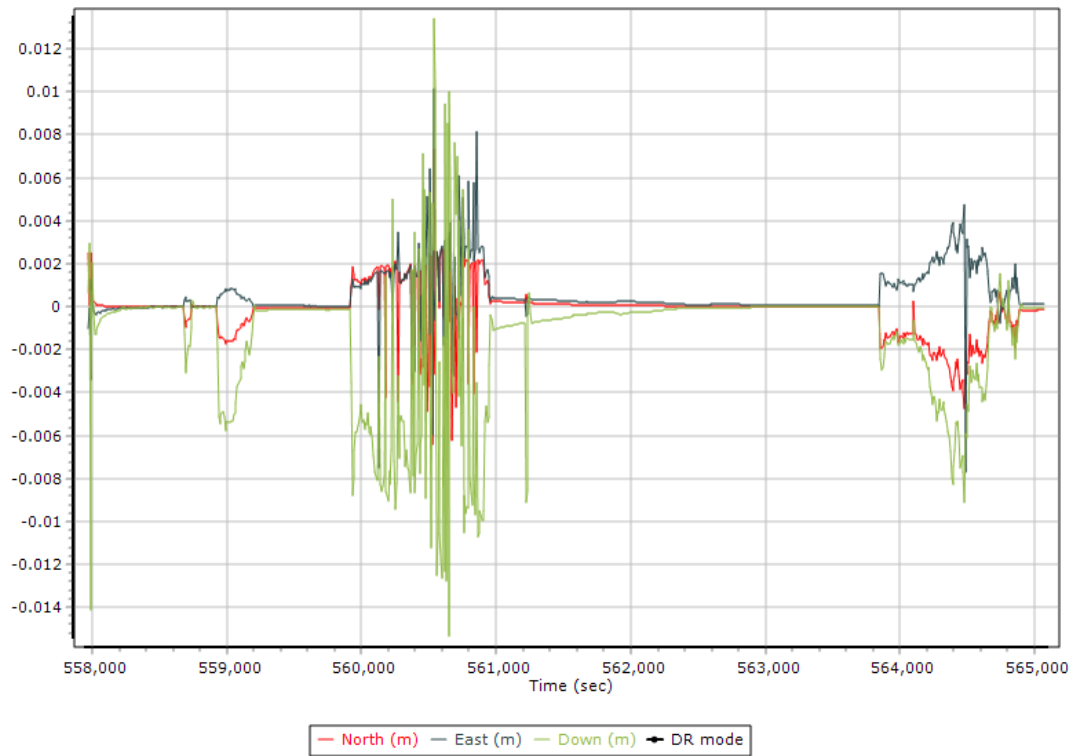
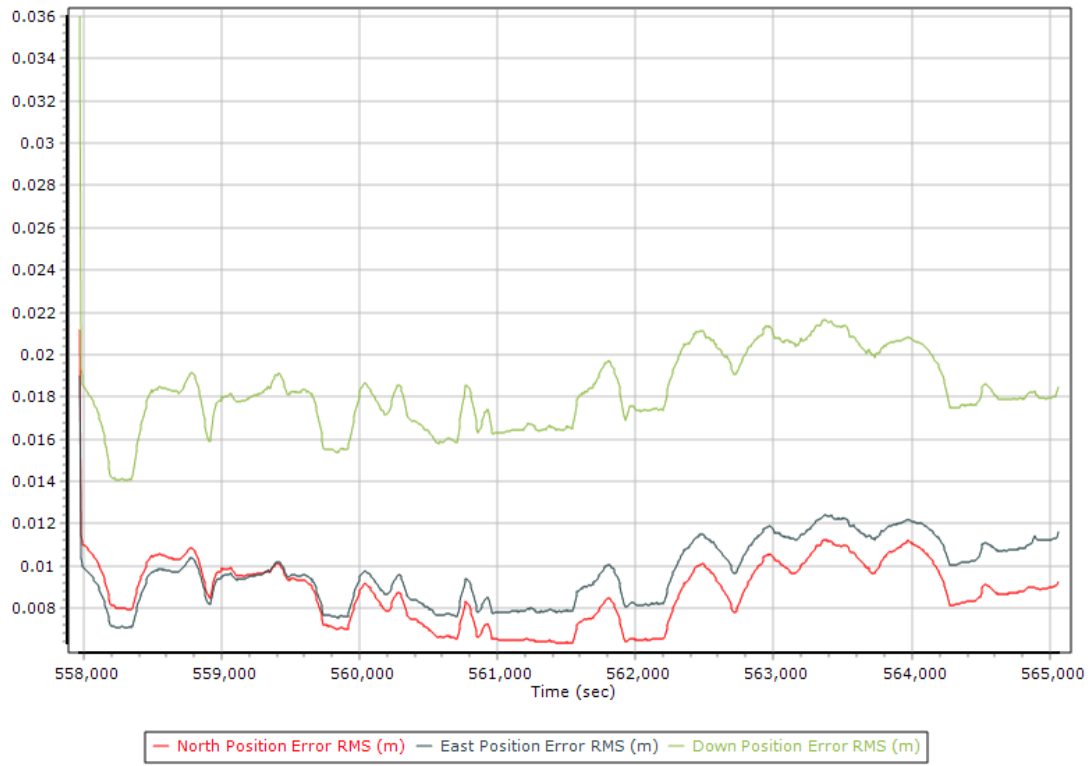
Entire time interval
 Seconds of start week

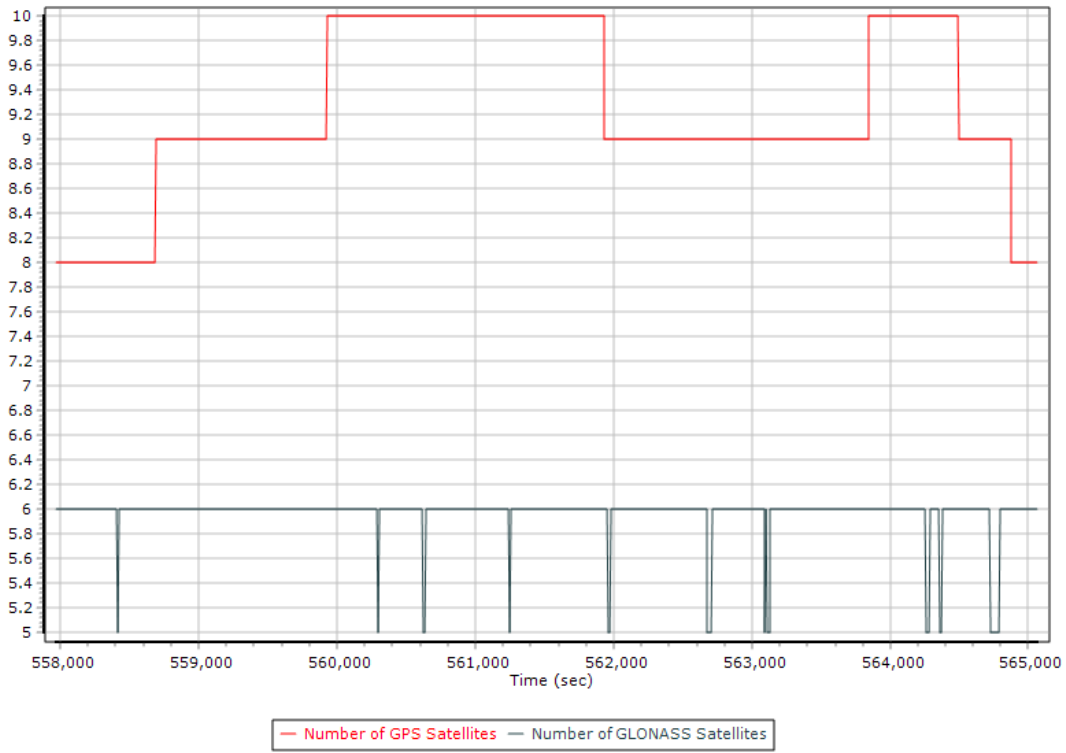
UTC Offset: 18.000

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

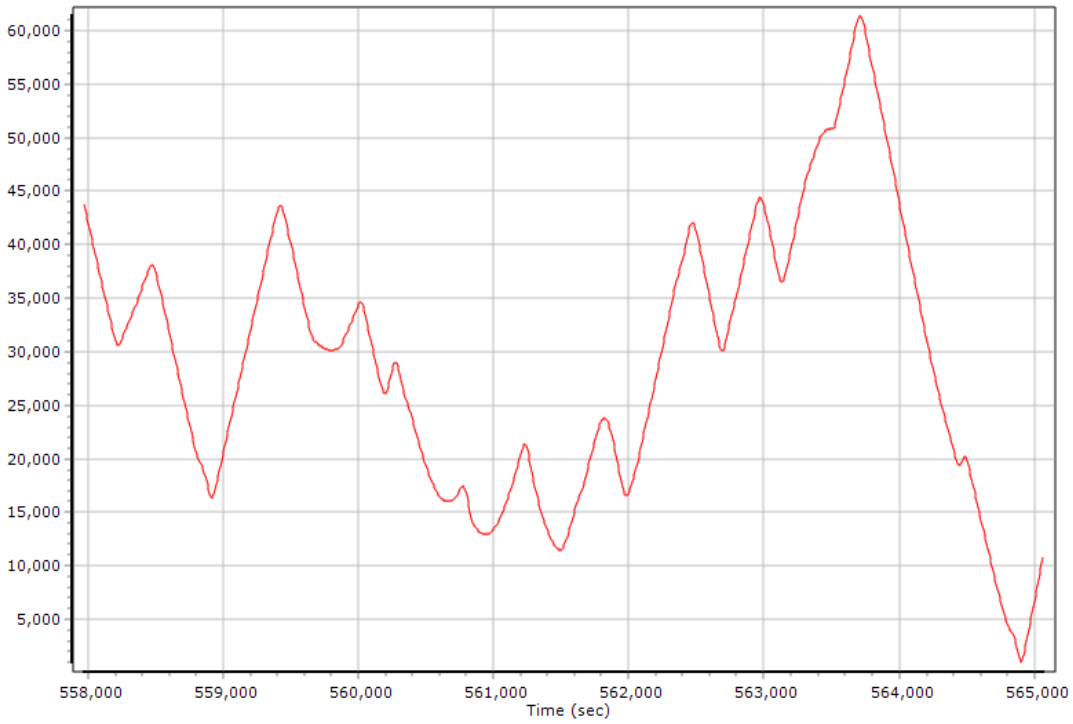
OK Cancel

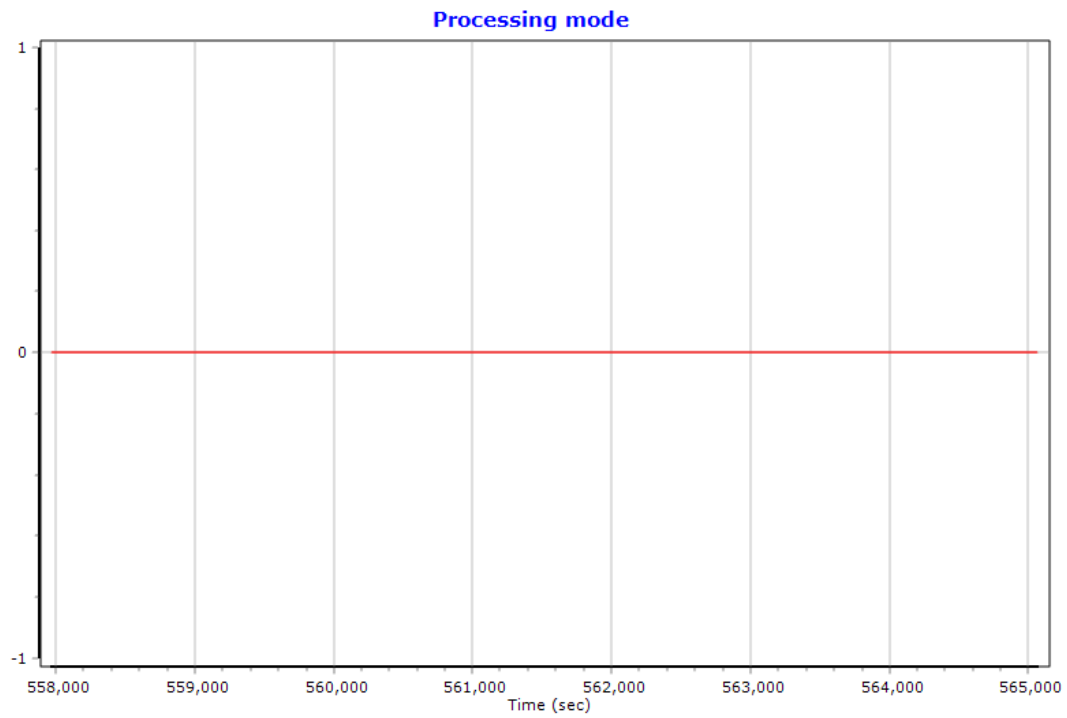
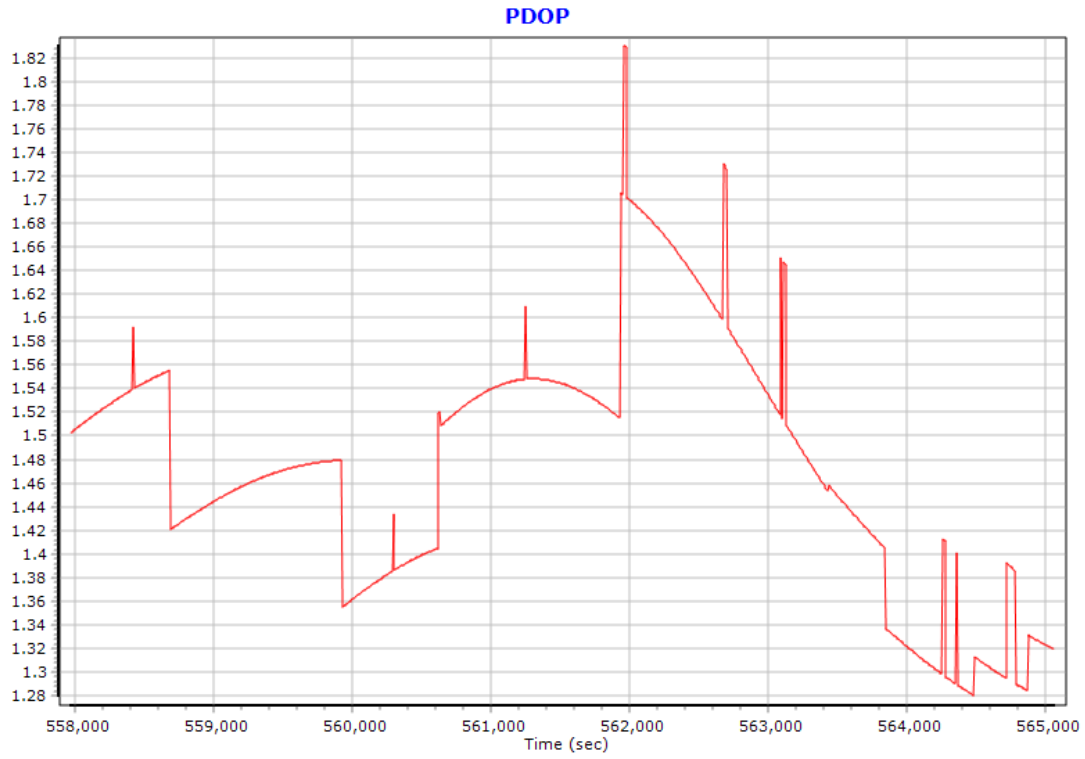






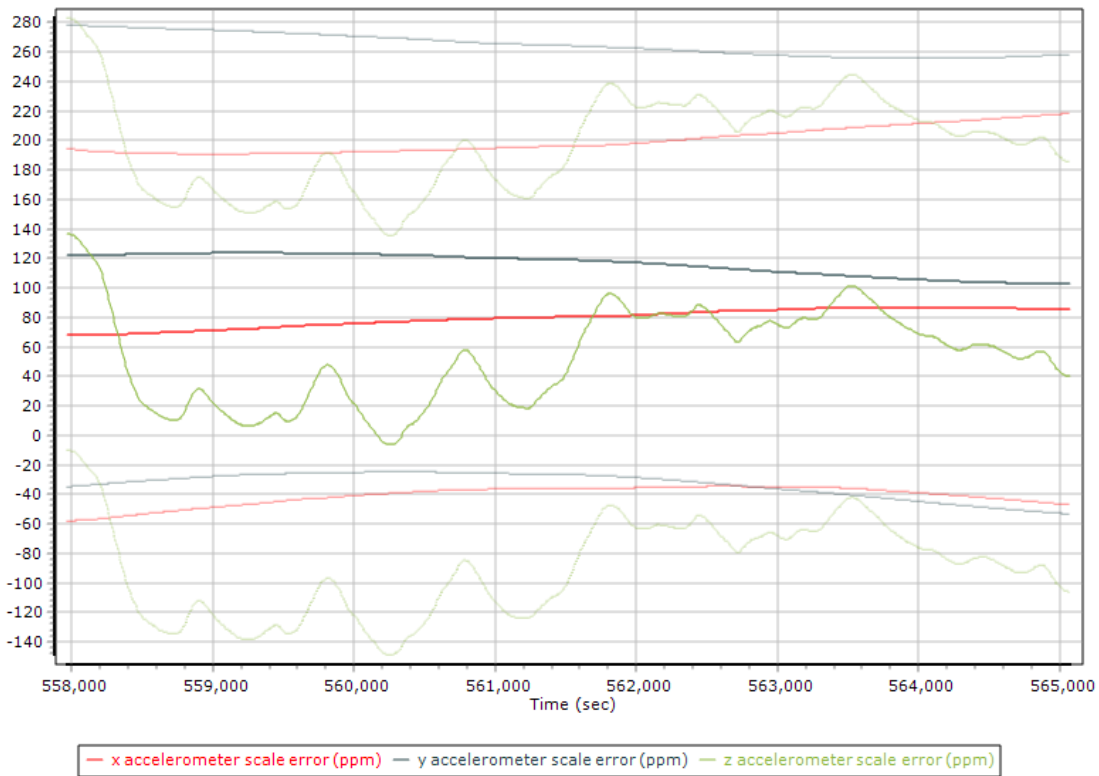
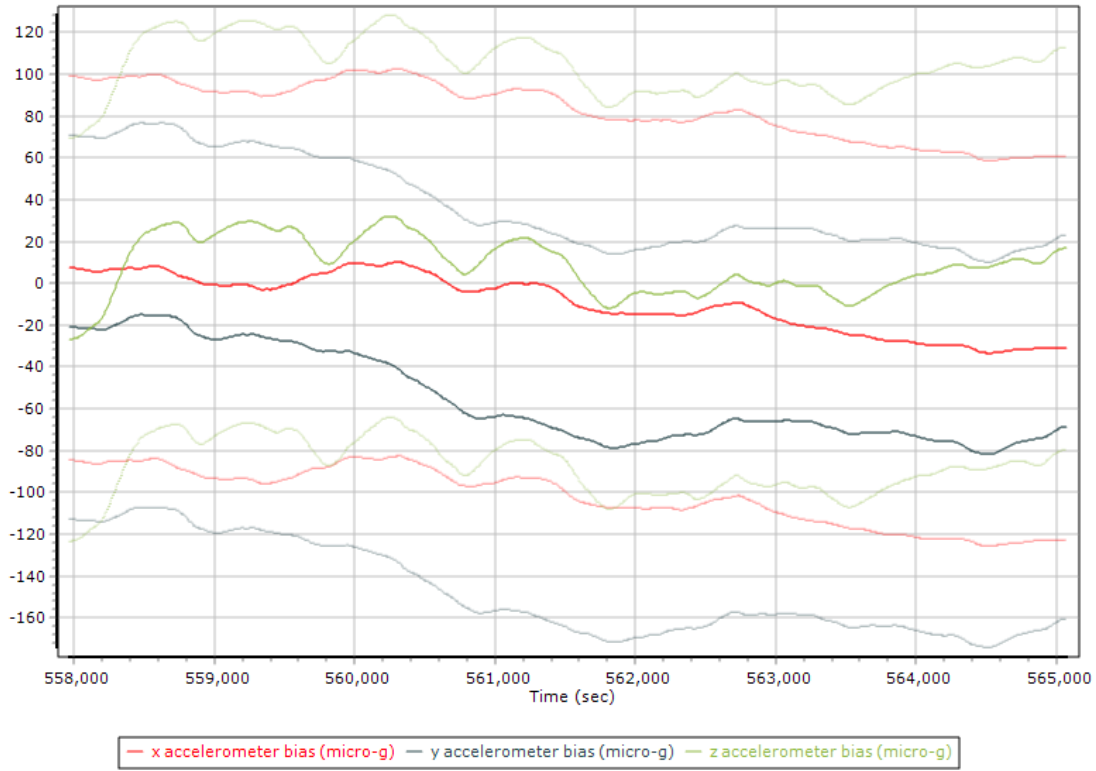
Baseline Length (m)

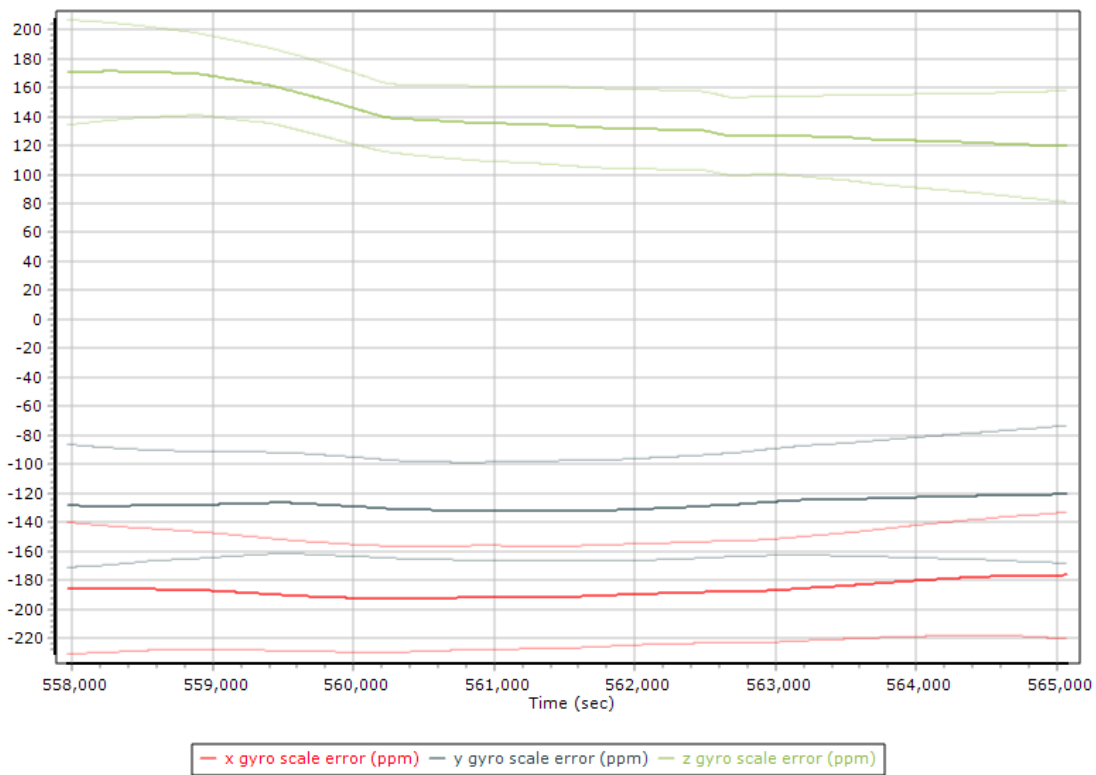
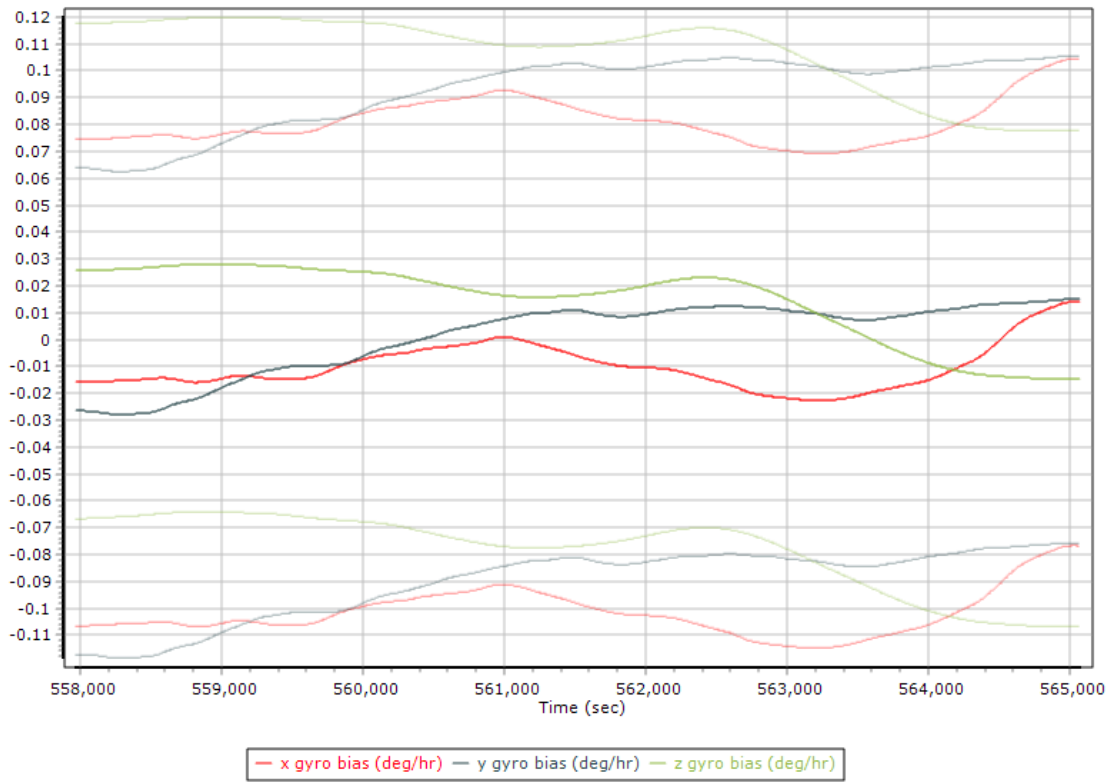




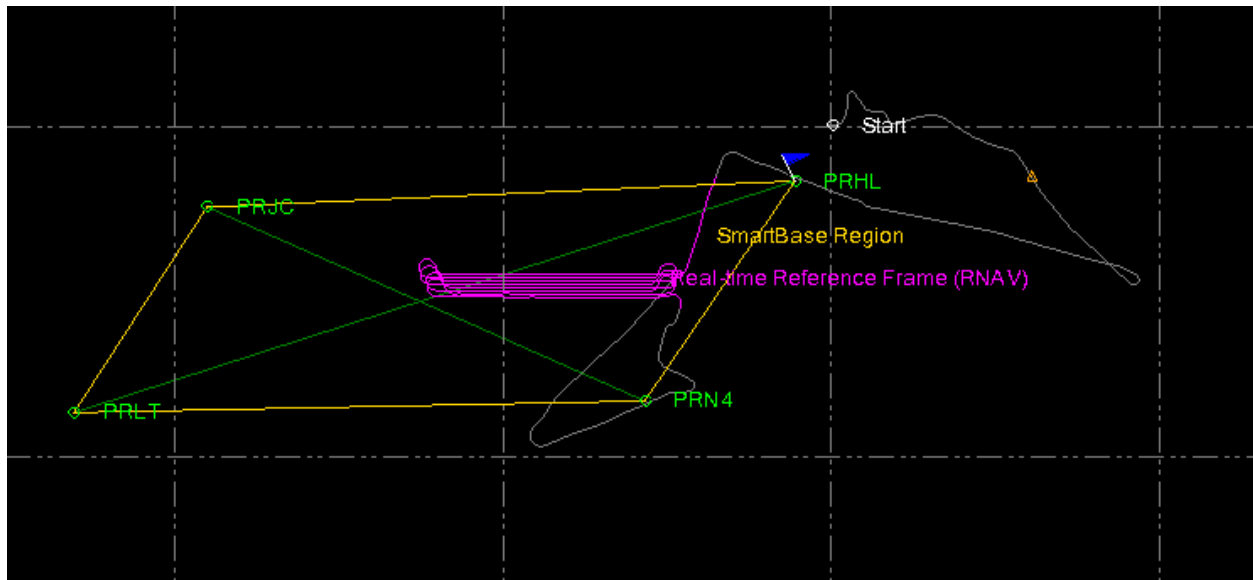
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





RBV18169A



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: -0.037 m	X: 0.000 deg
Y: 0.007 m	Y: 0.000 deg
Z: -0.985 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

Project Settings interface showing a sidebar menu and a main configuration panel.

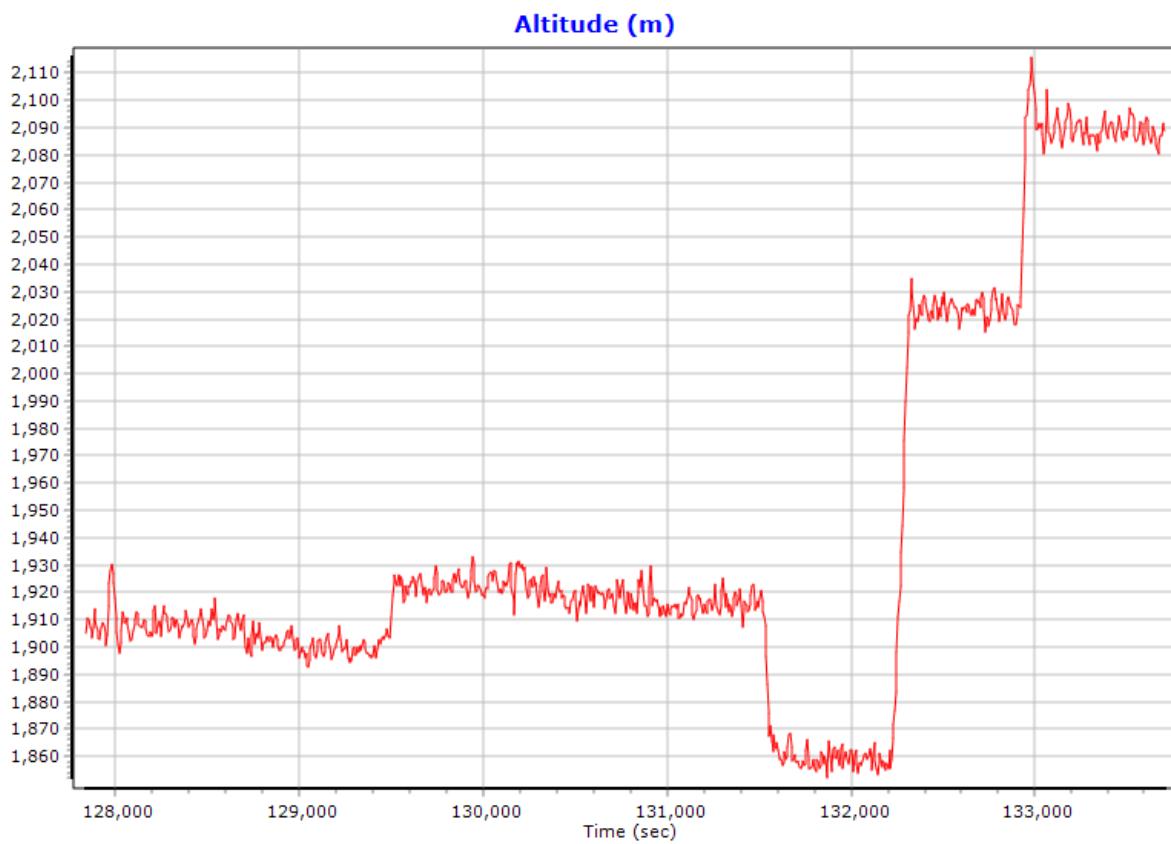
Timing

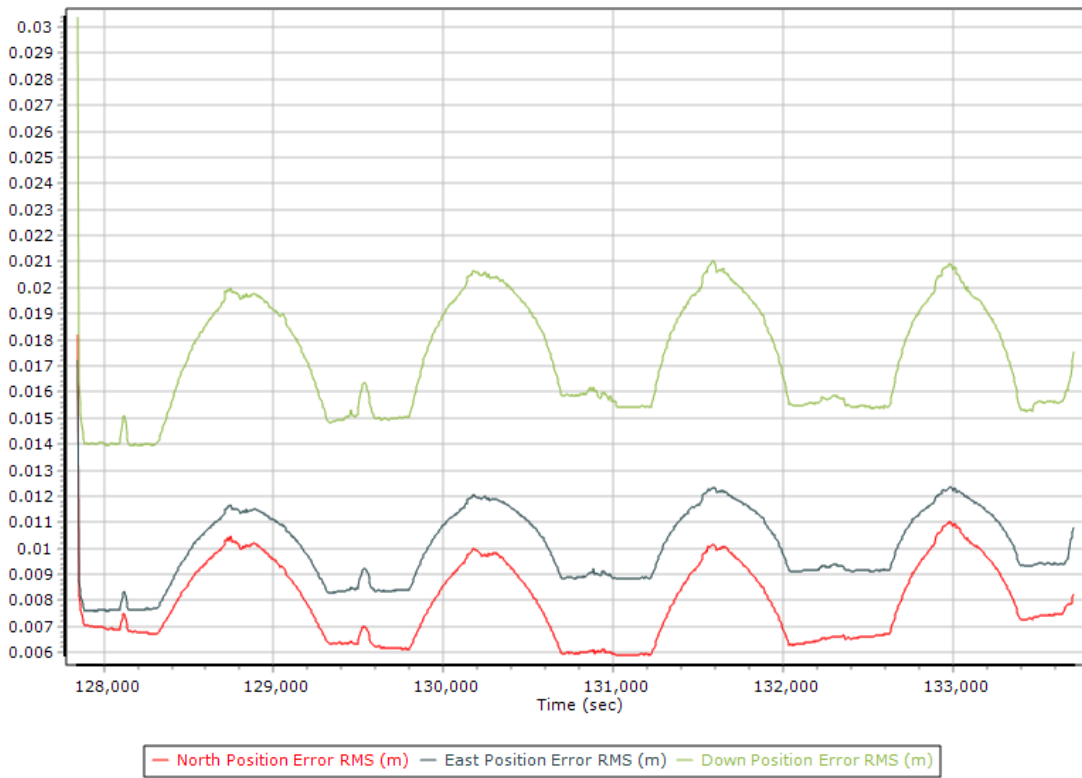
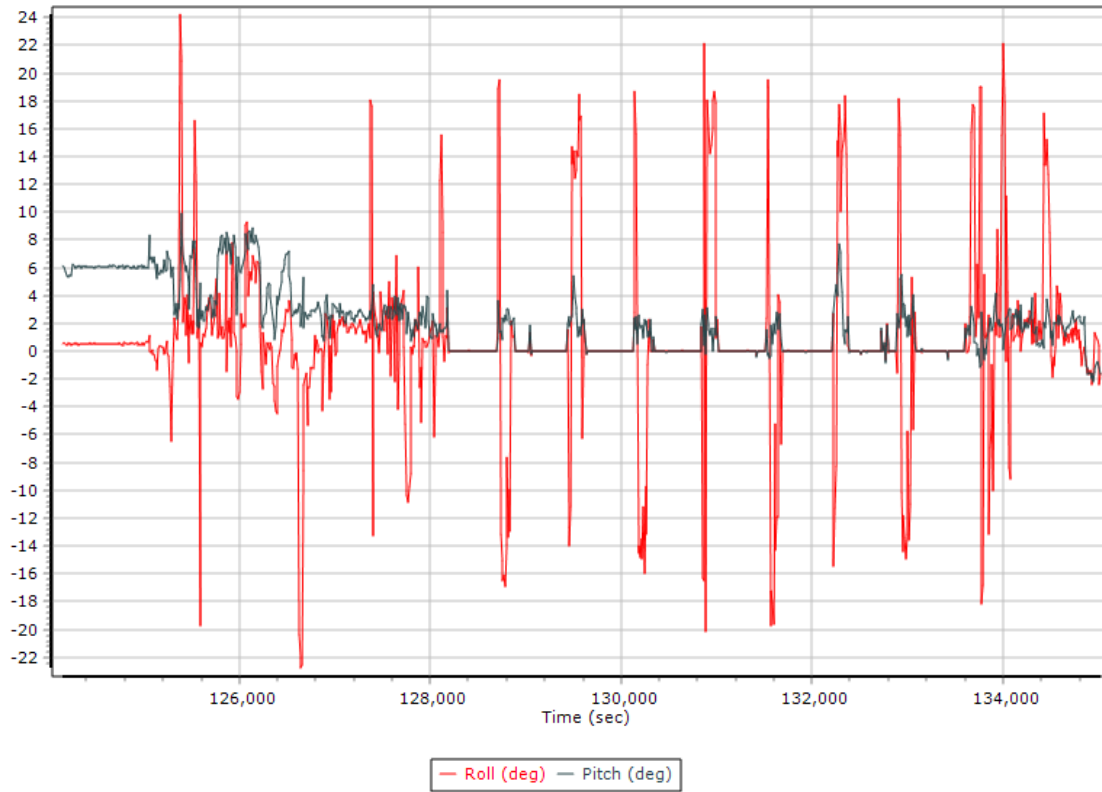
Start: 127842.581
End: 133720.960

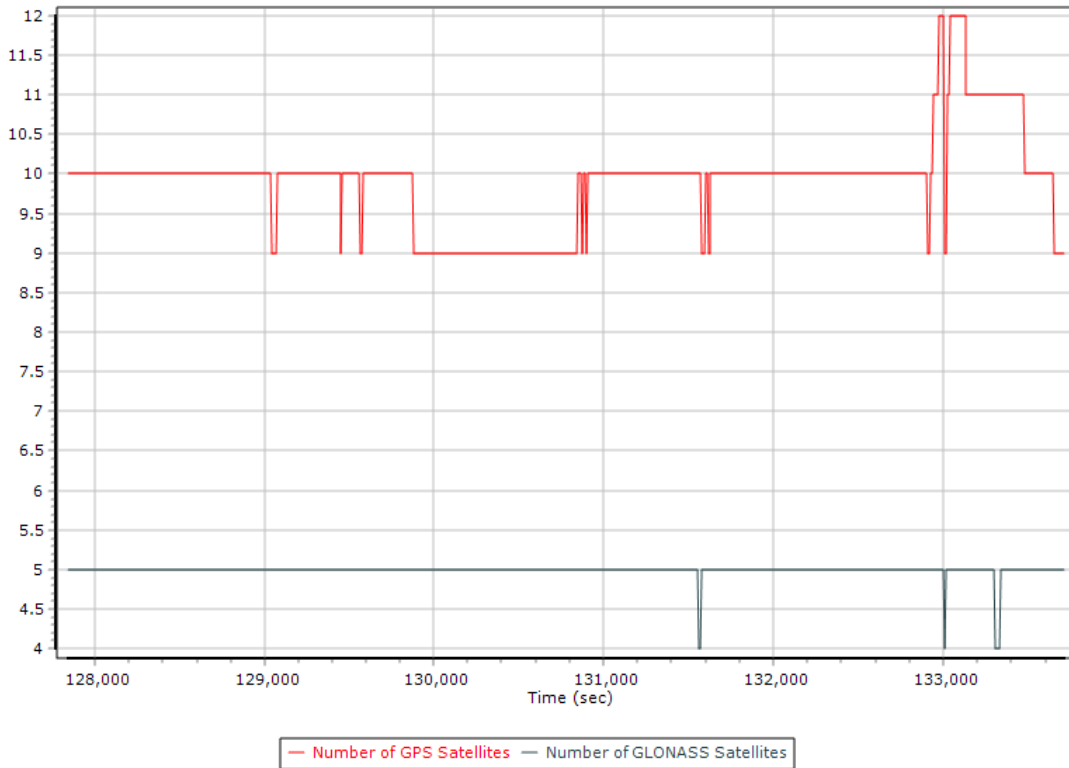
Entire time interval
 Seconds of start week

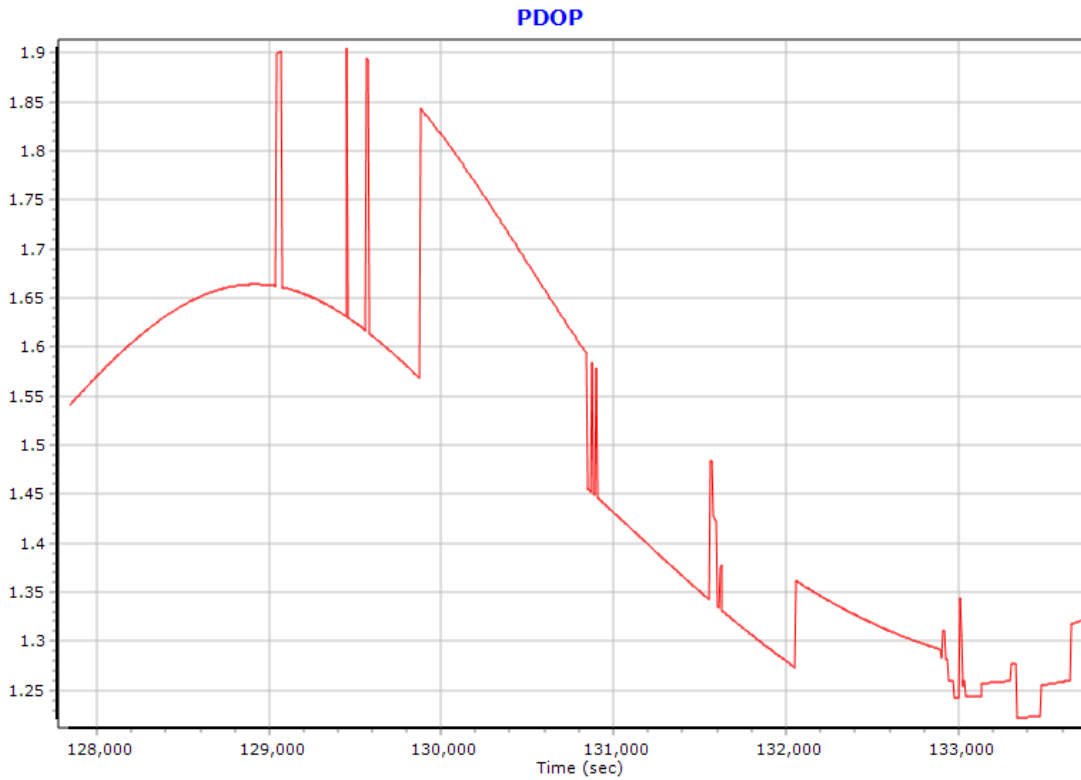
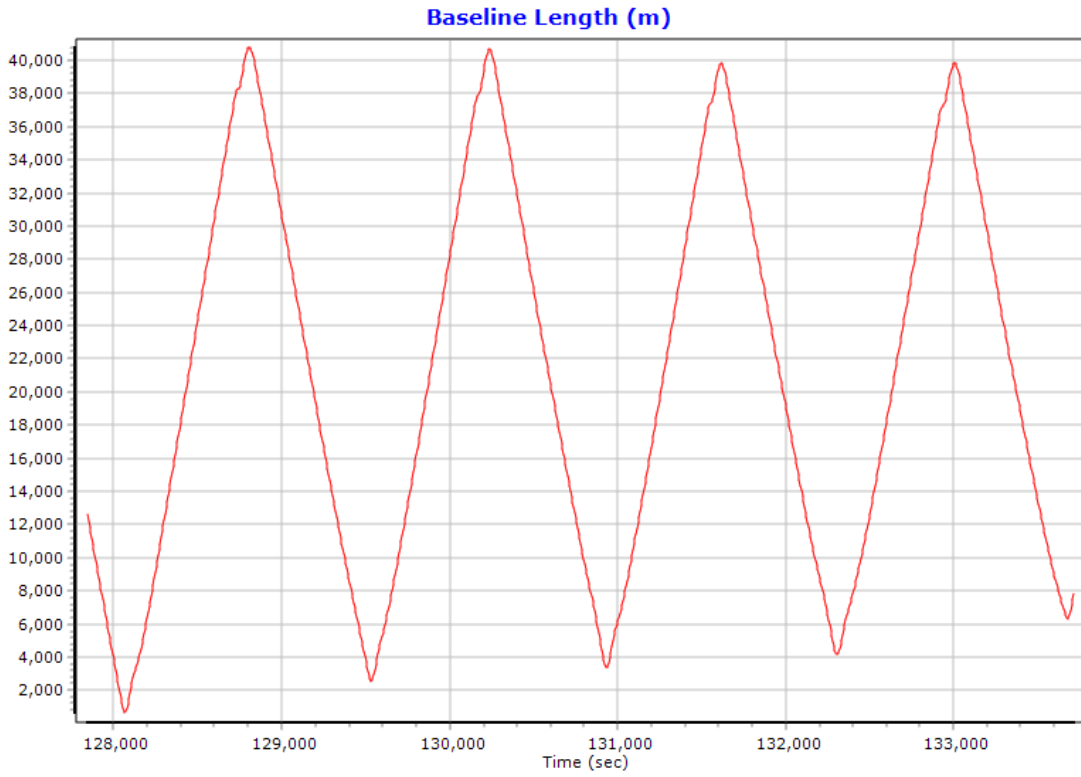
UTC Offset: 18.000

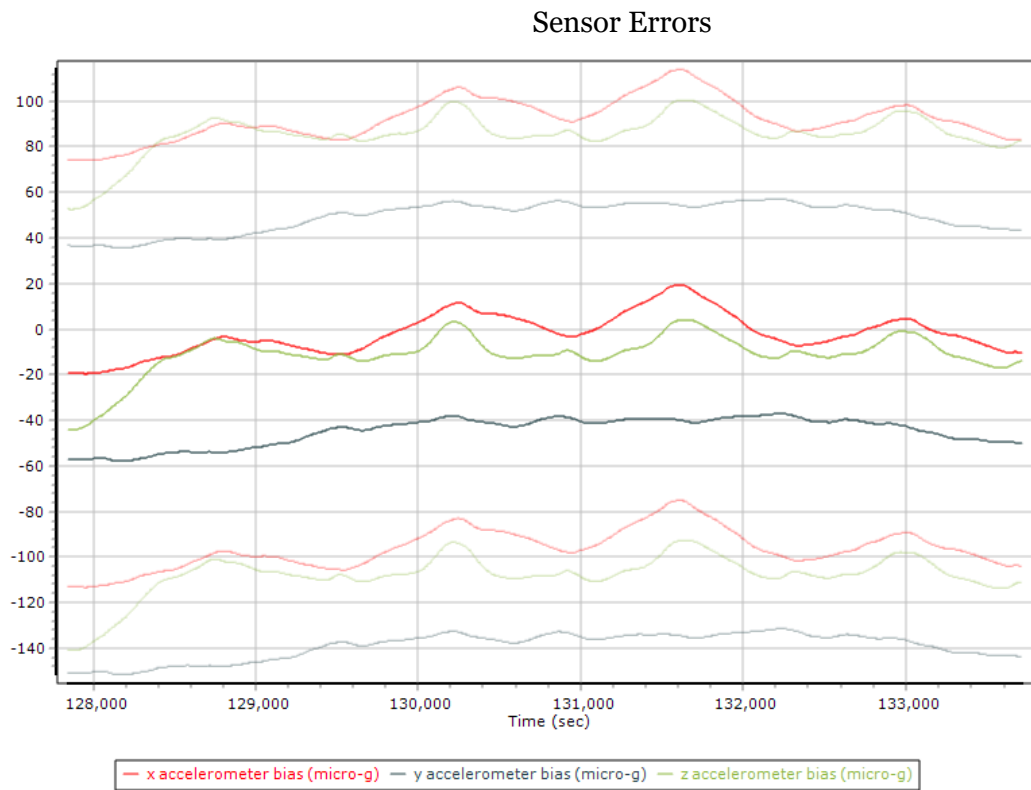
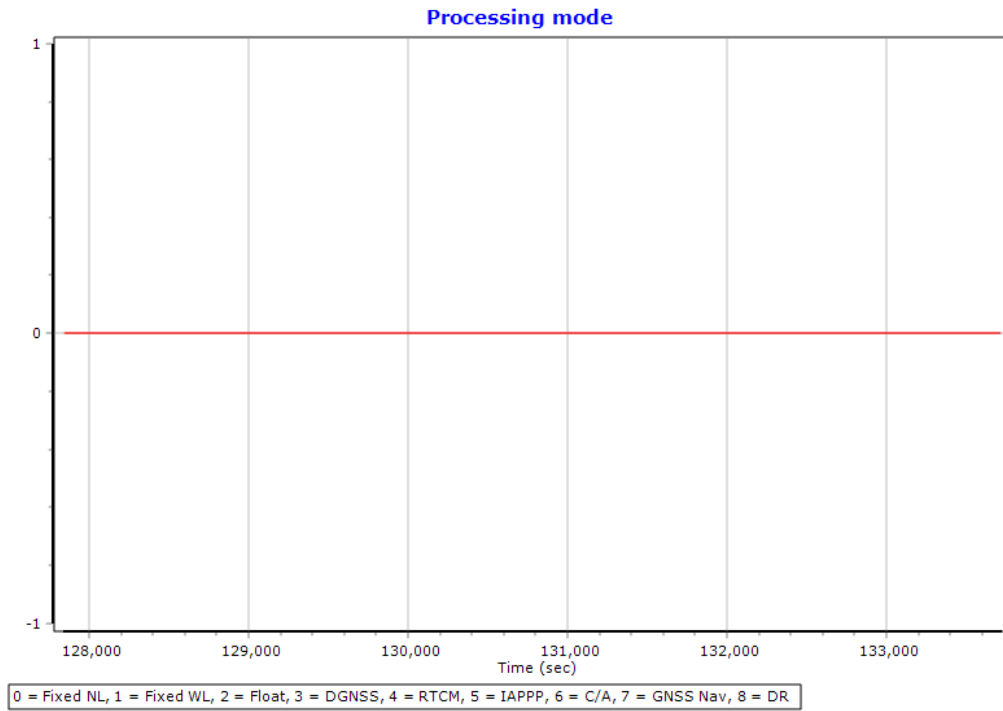
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

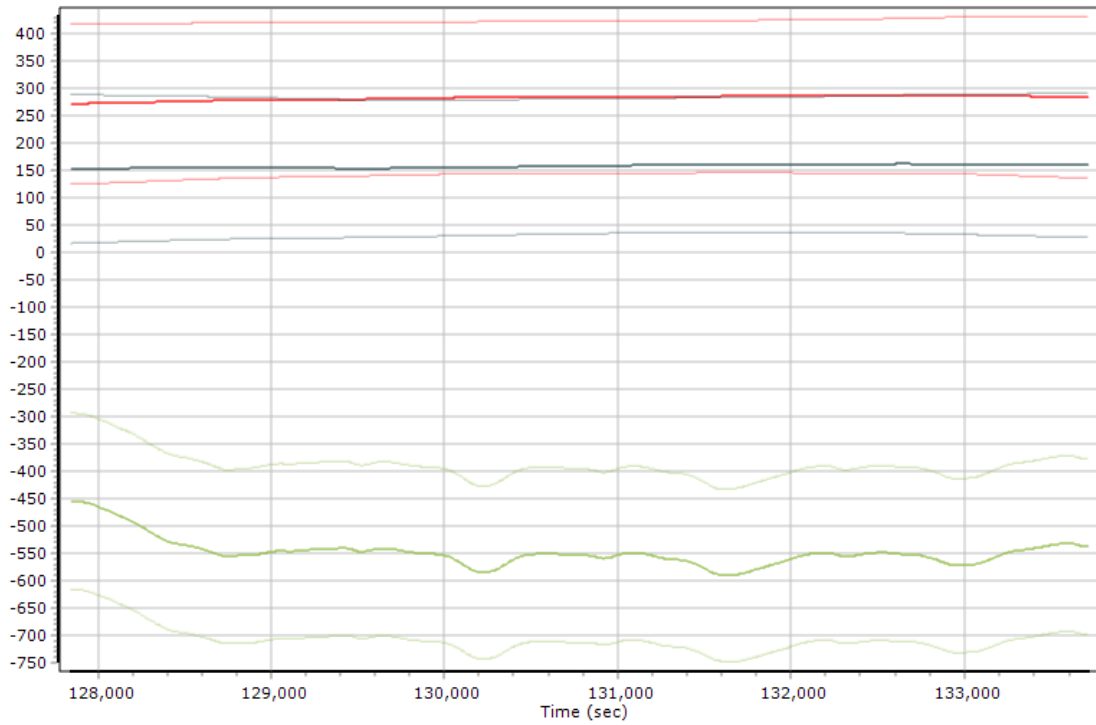




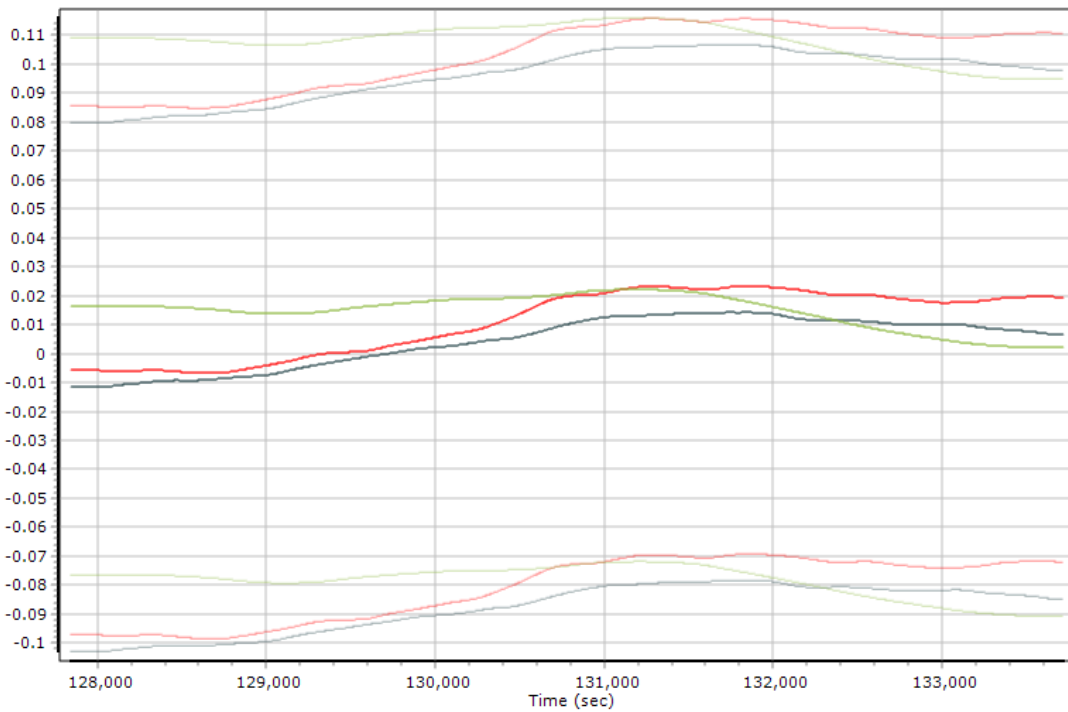




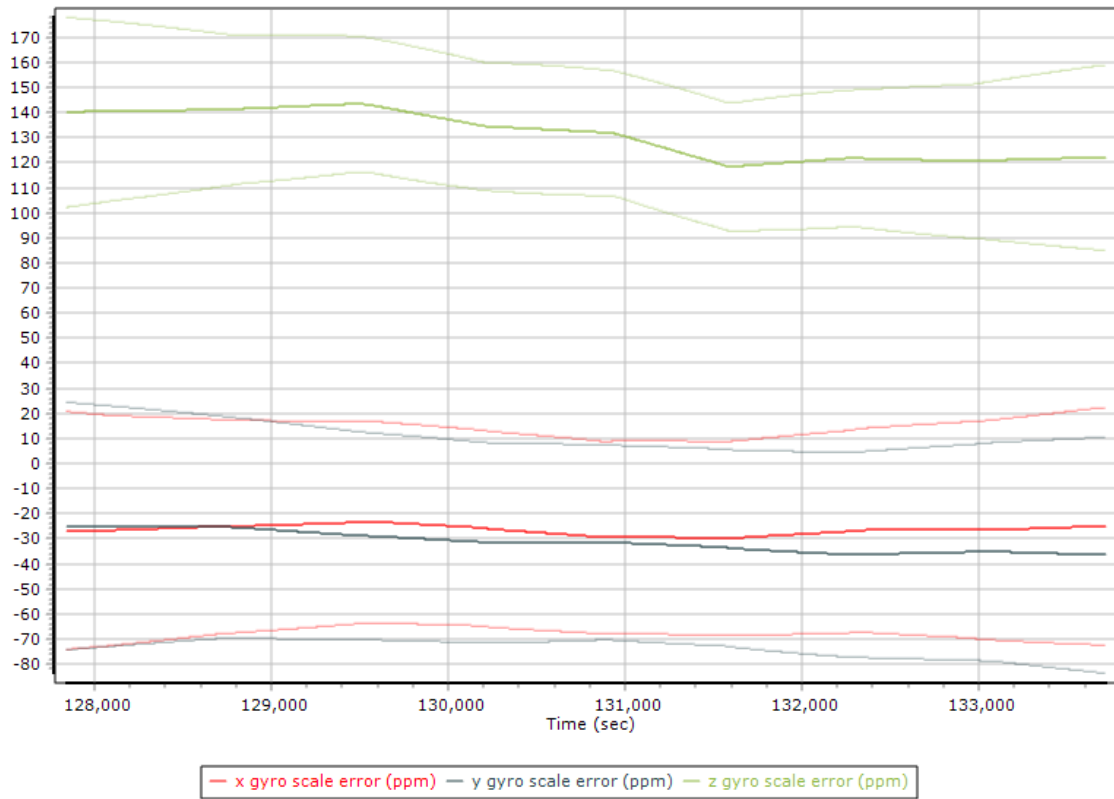




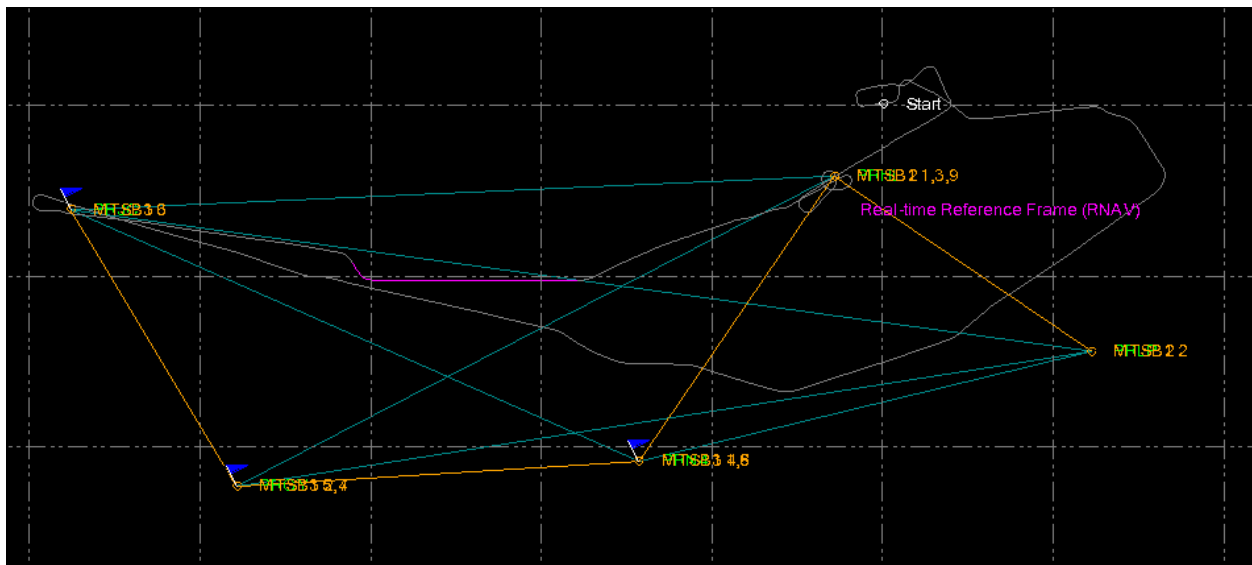
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



RBV18170A



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: -0.034 m
Y: -0.010 m
Z: -0.352 m

Stabilized Mount to IMU Mounting Angles

X: 0.000 deg
Y: 0.000 deg
Z: 0.000 deg

Stabilized Mount to Primary GNSS Lever Arm

X: -0.037 m
Y: 0.007 m
Z: -0.985 m

Aircraft to Stabilized Mount Mounting Angles

X: 0.000 deg
Y: 0.000 deg
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: 216765.047
End: 217283.169

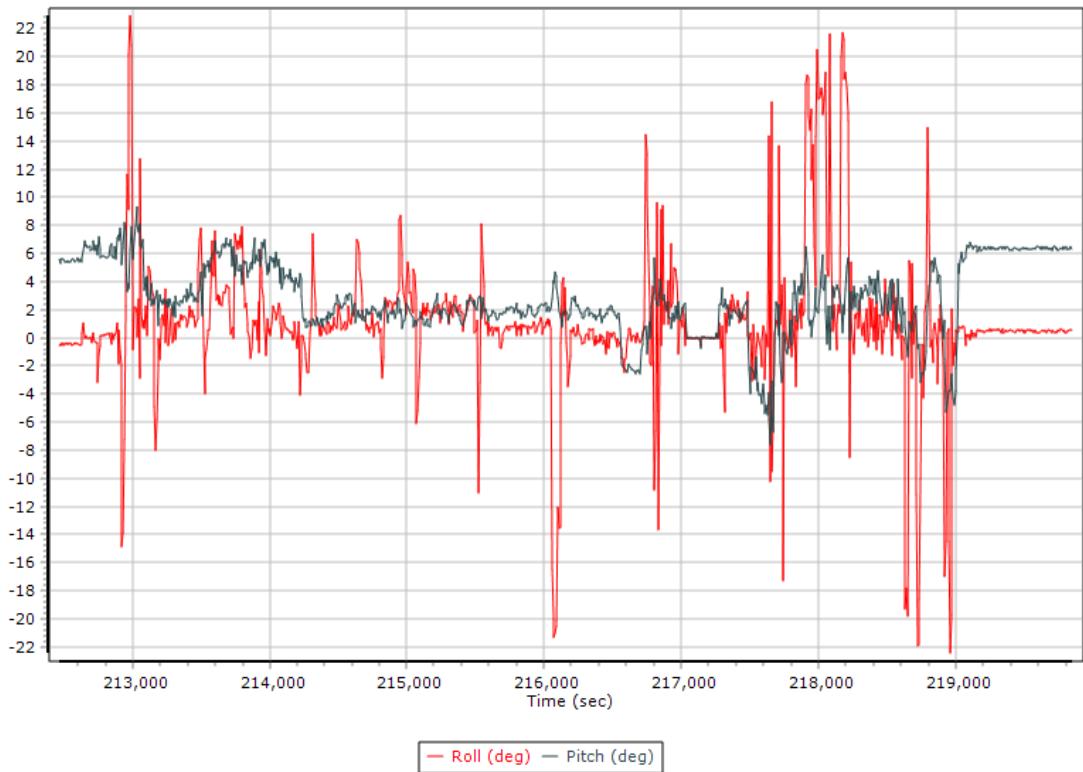
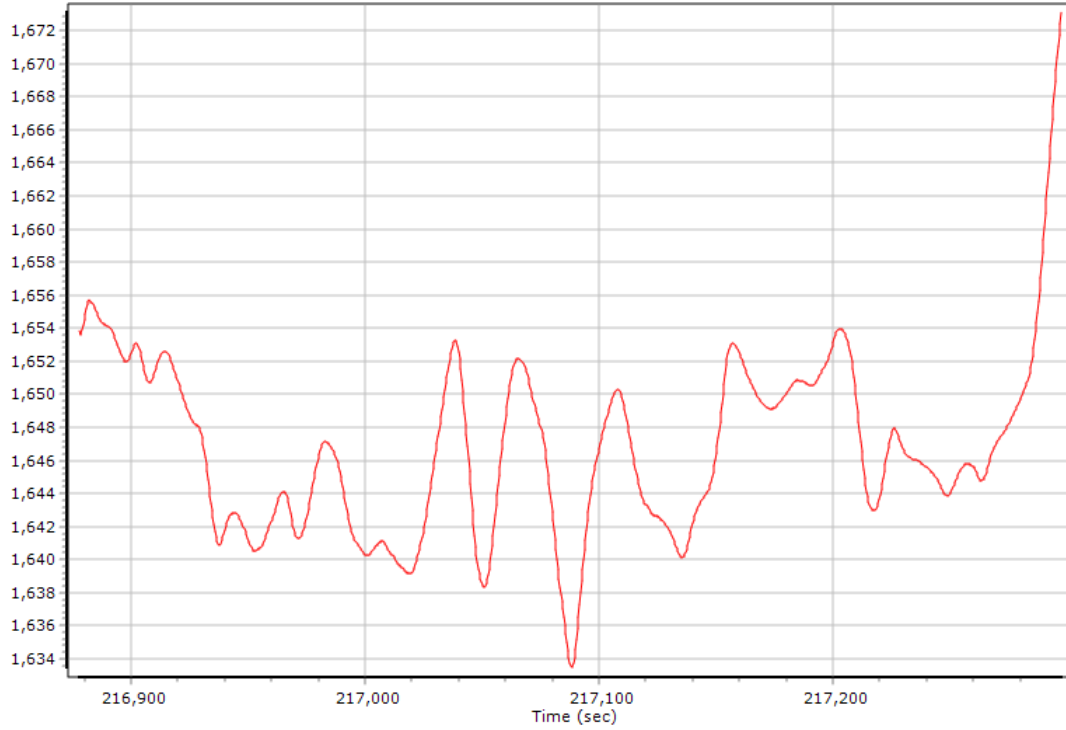
Entire time interval
 Seconds of start week

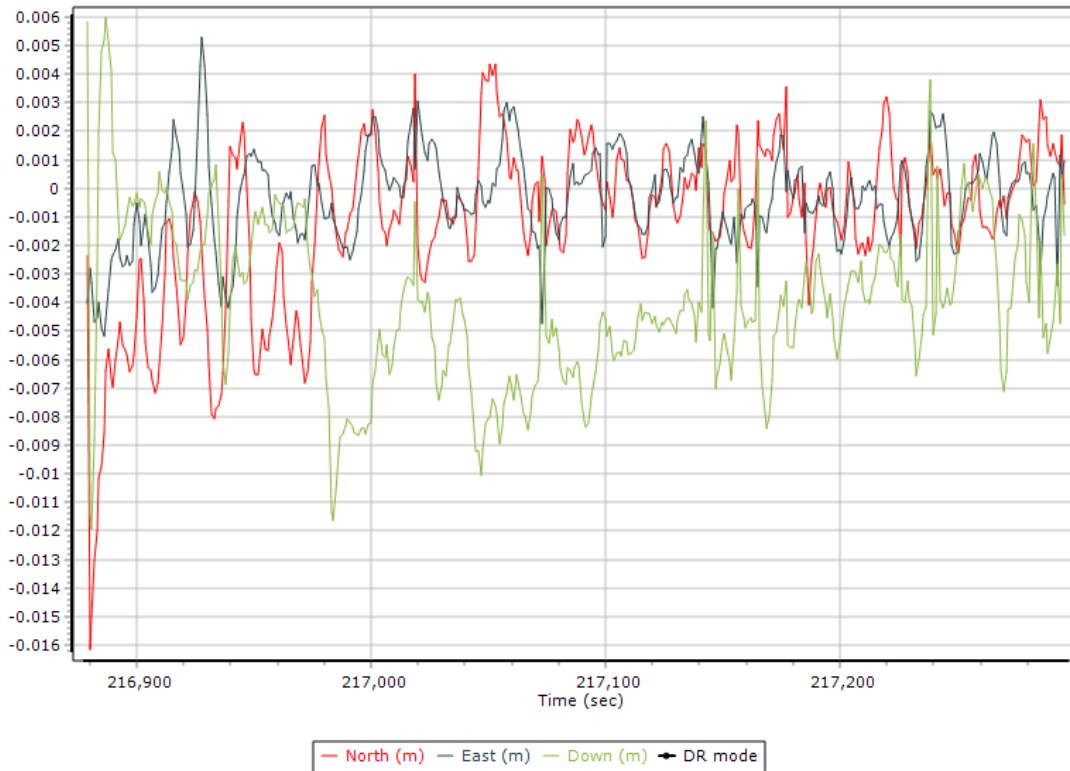
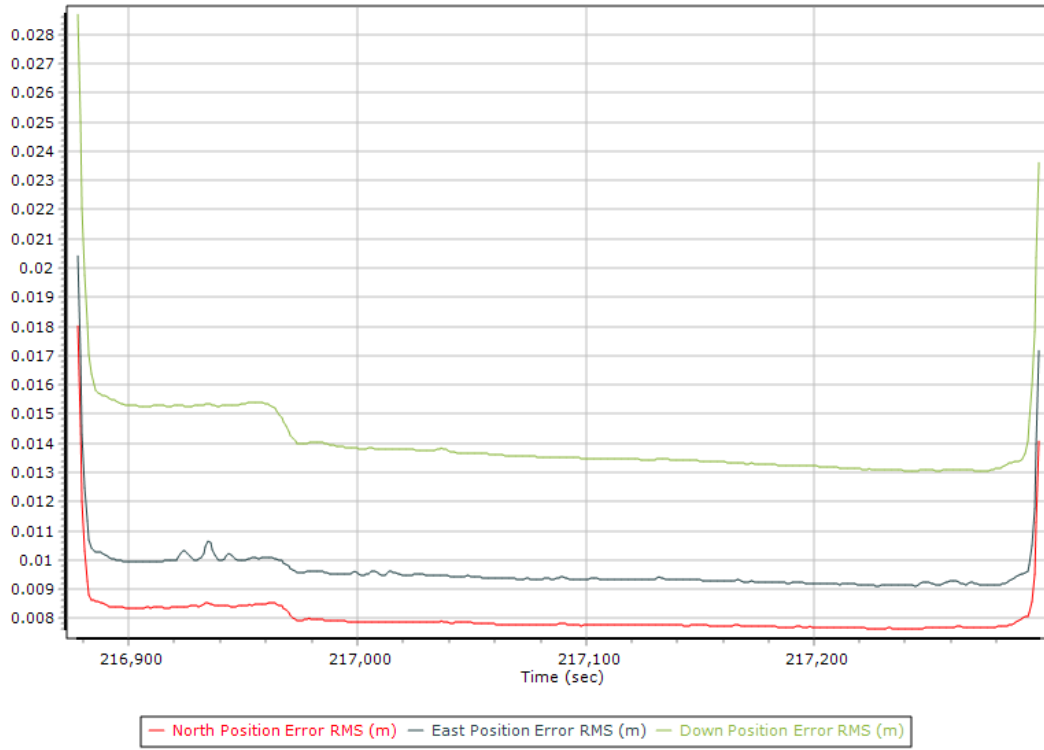
UTC Offset: 18.000

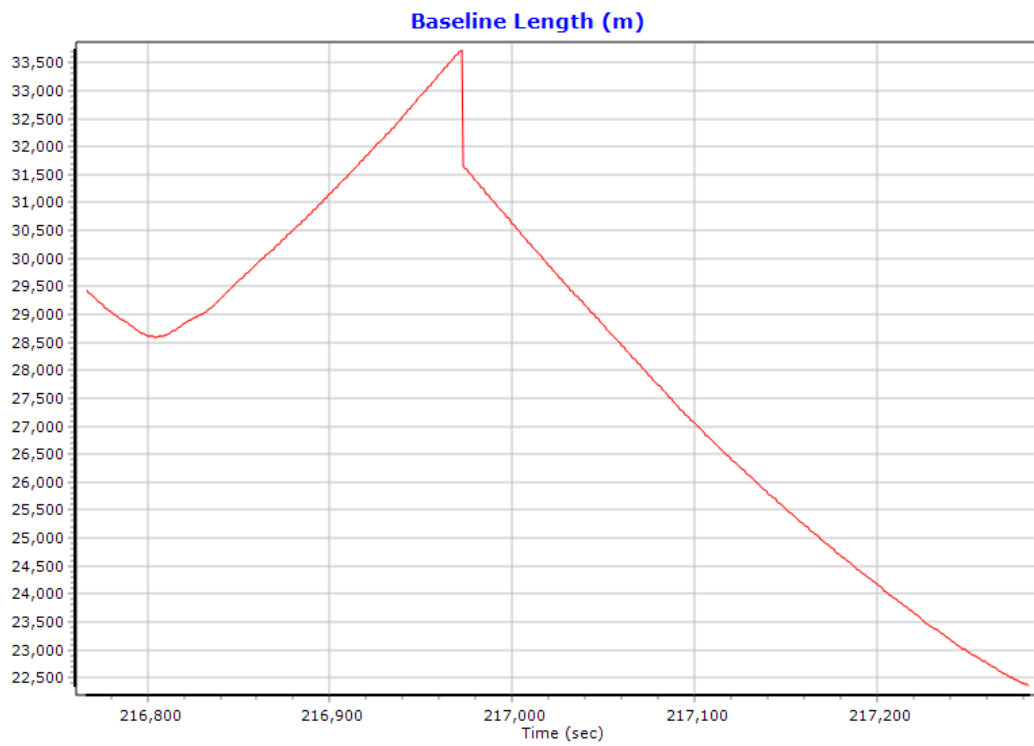
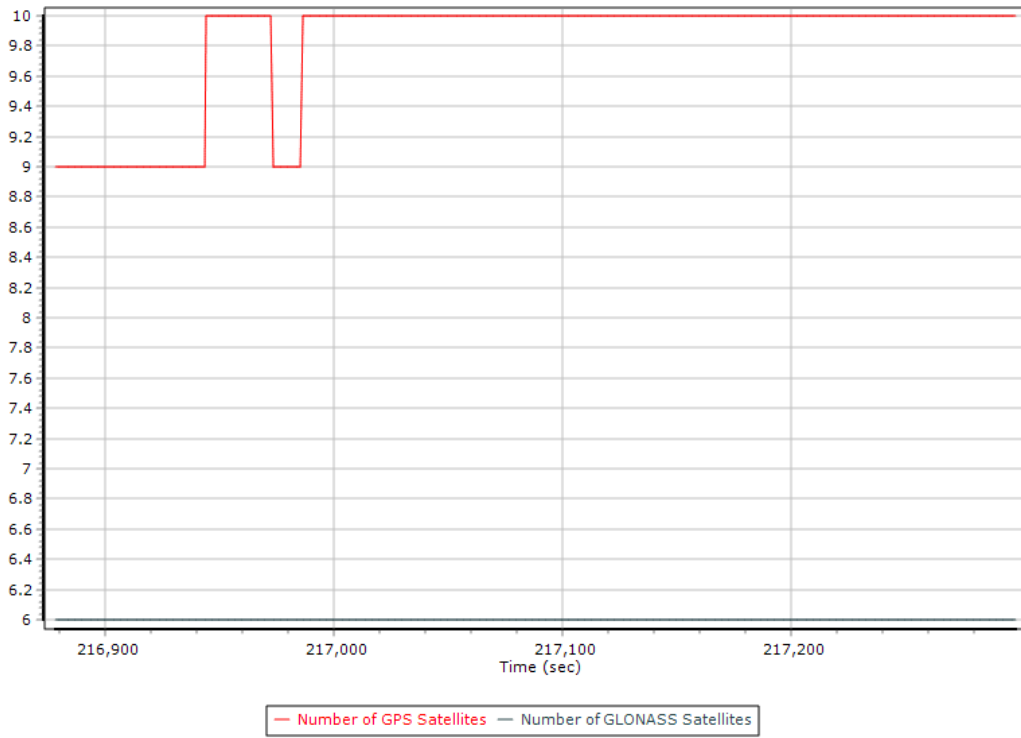
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

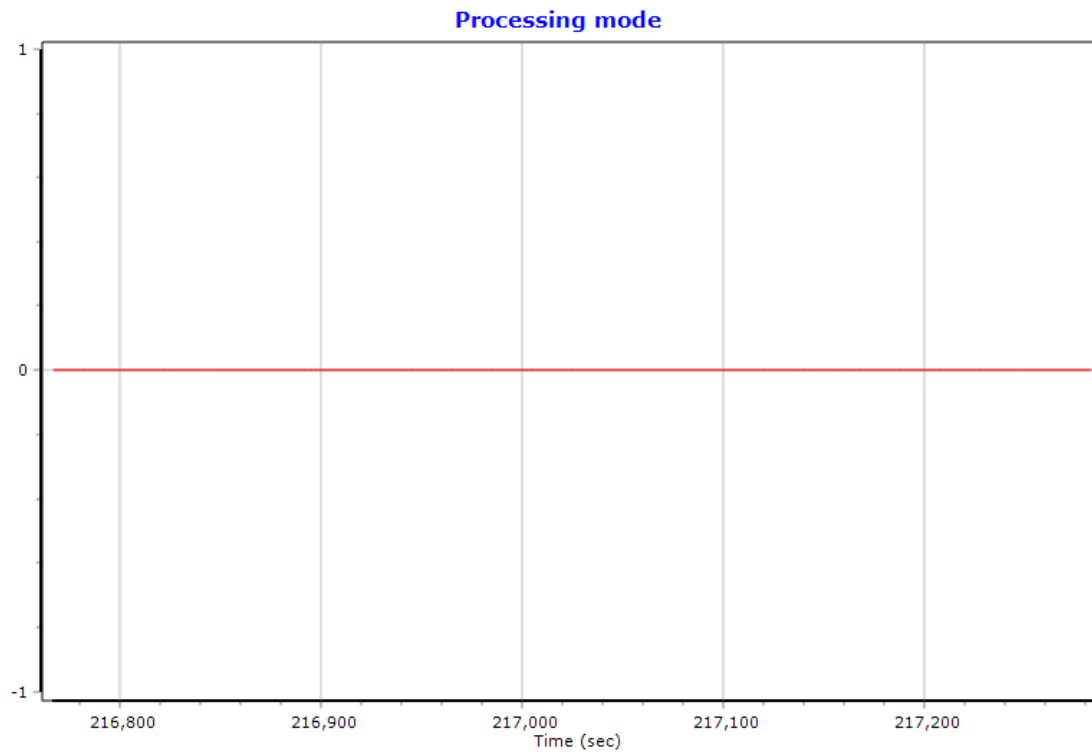
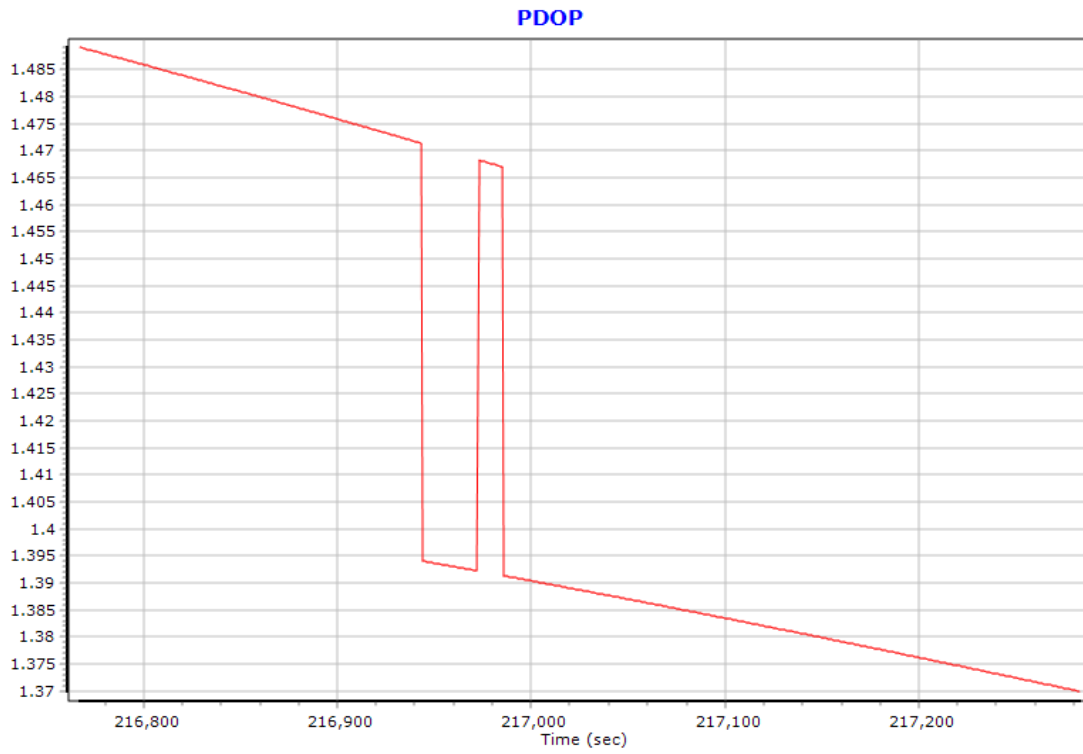
OK Cancel

Altitude (m)



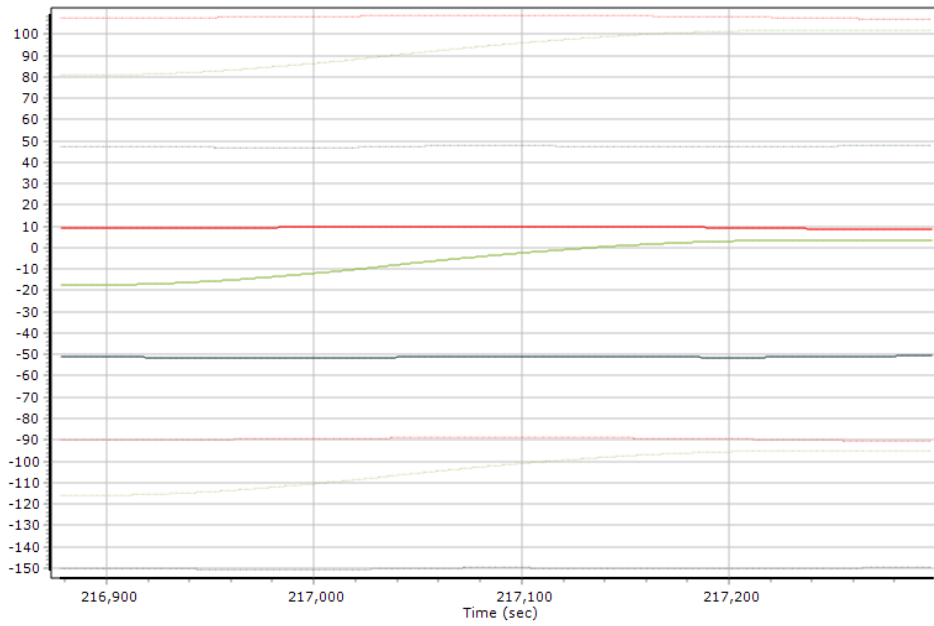




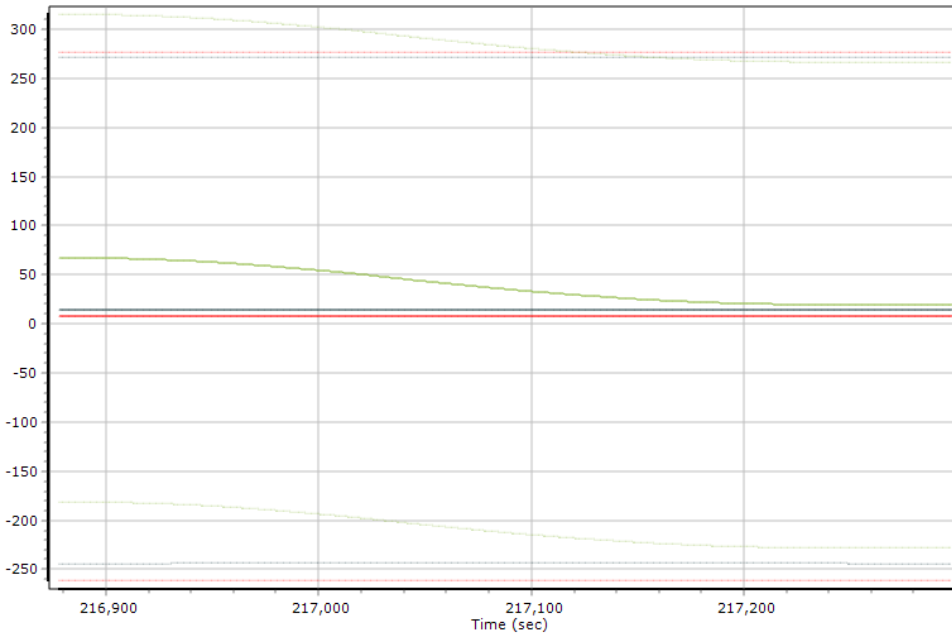


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

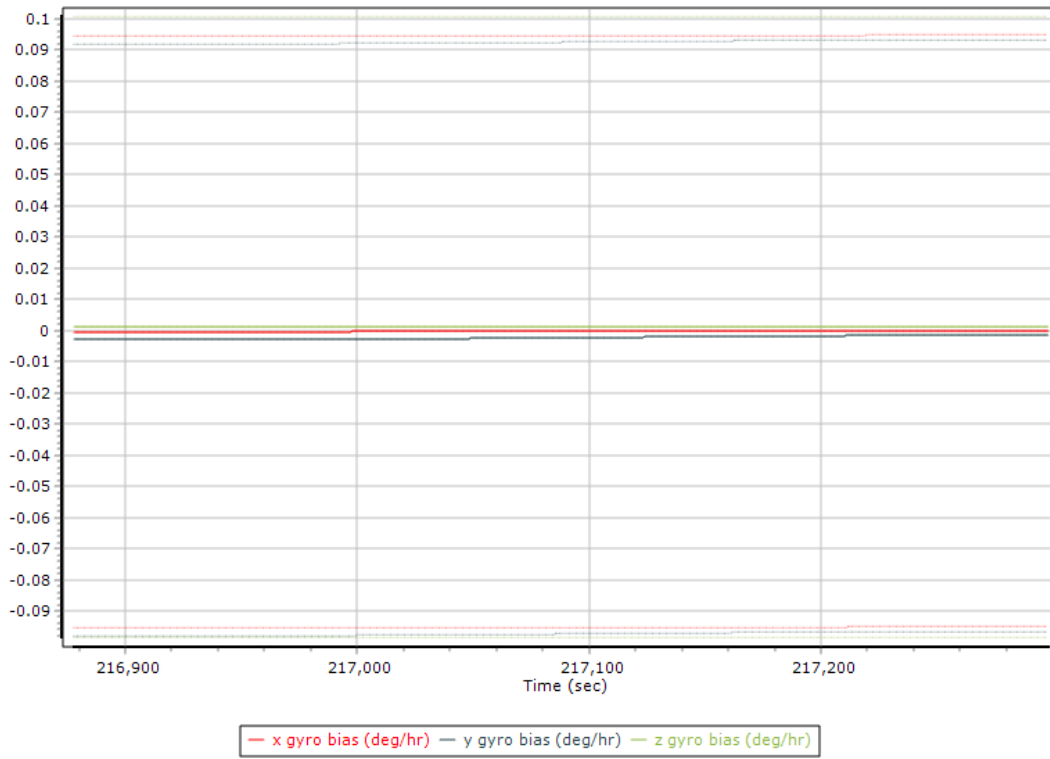
Sensor Errors



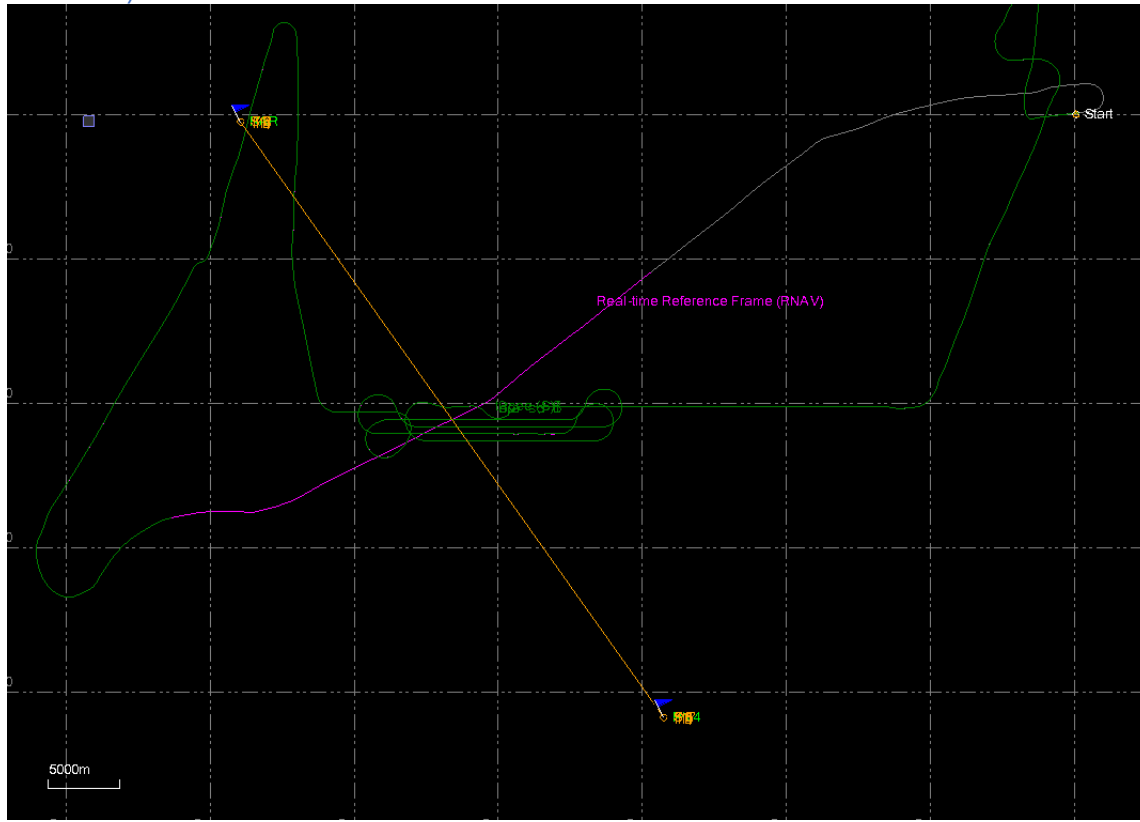
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



RBV18172A



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: -0.037 m	X: 0.000 deg
Y: 0.007 m	Y: 0.000 deg
Z: -0.985 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

Timing

Start

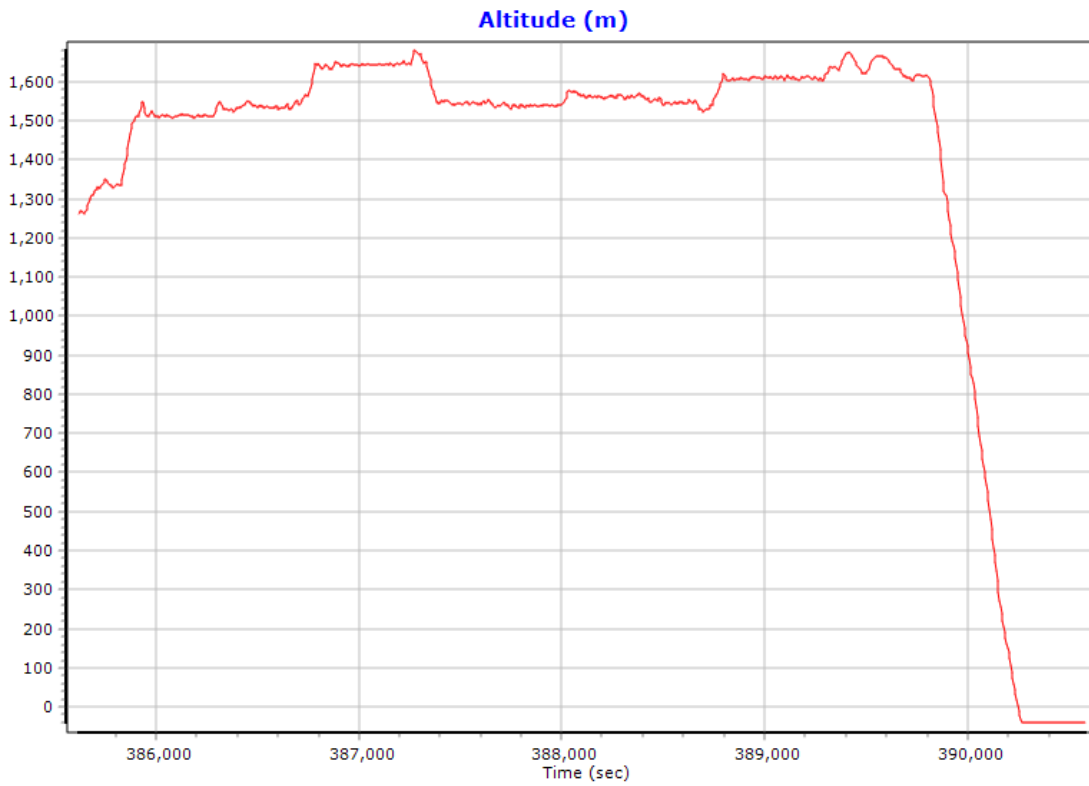
End

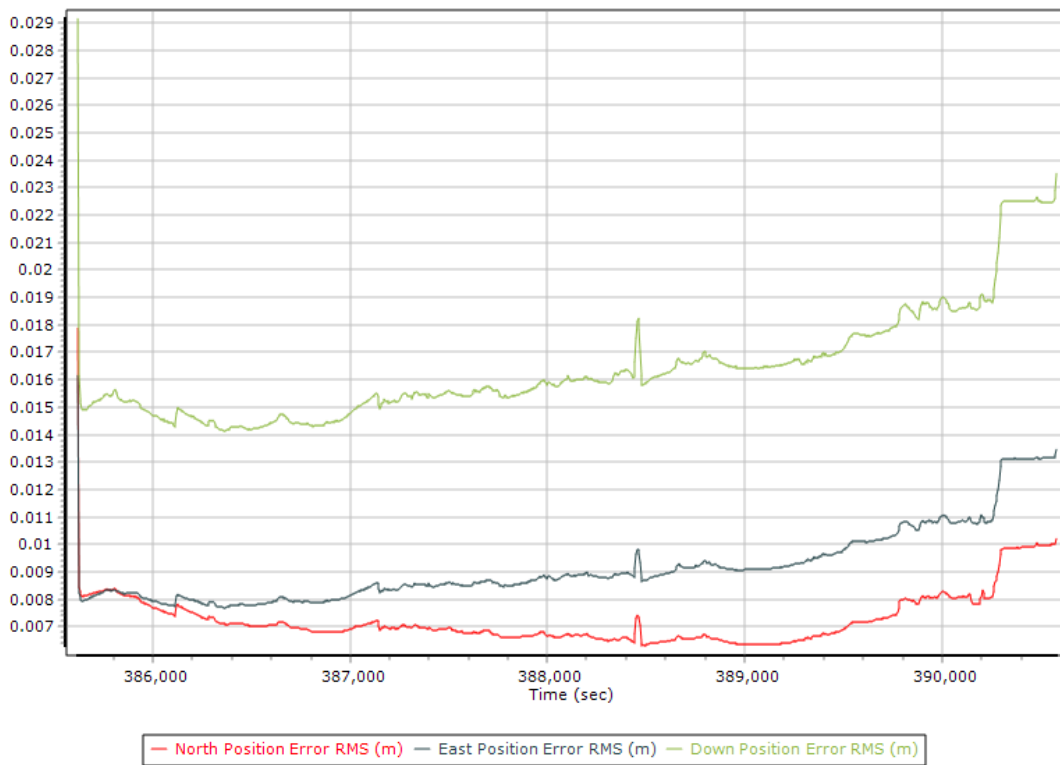
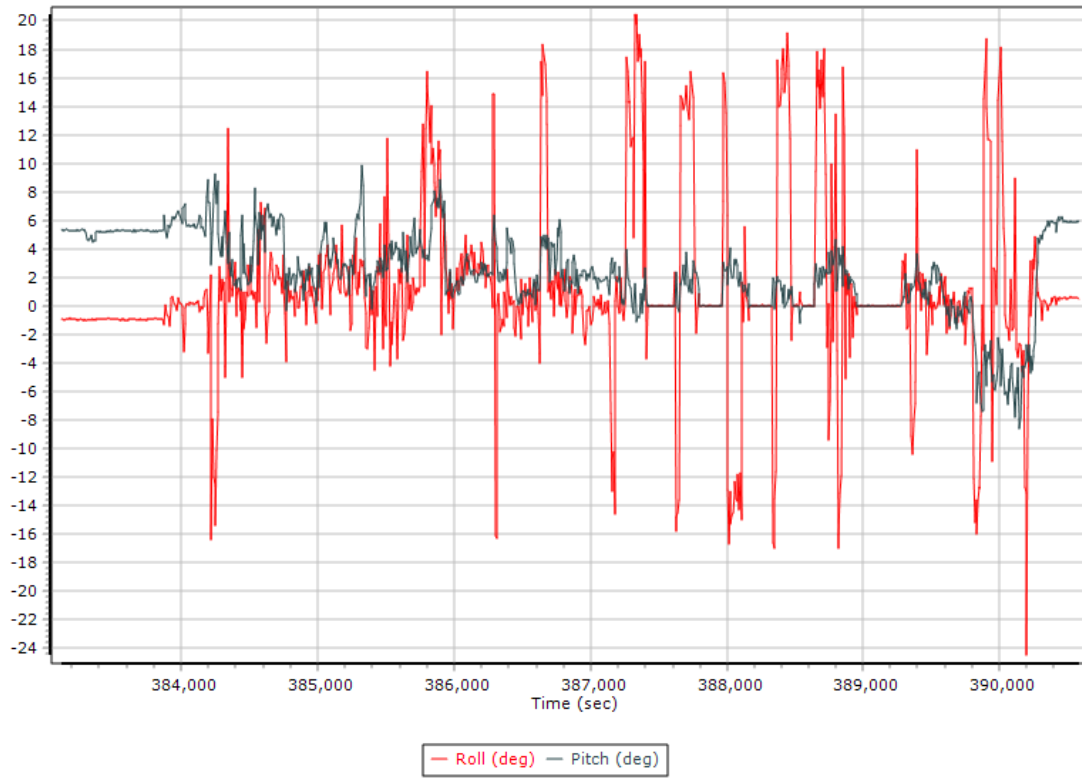
Entire time interval

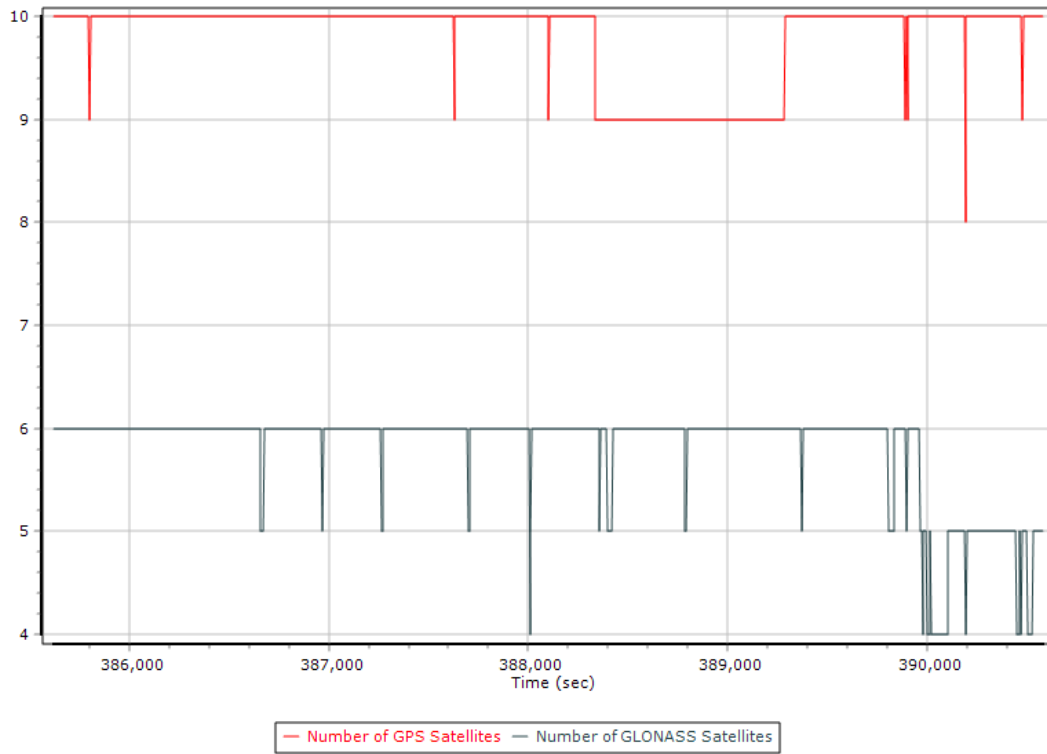
Seconds of start week

UTC Offset

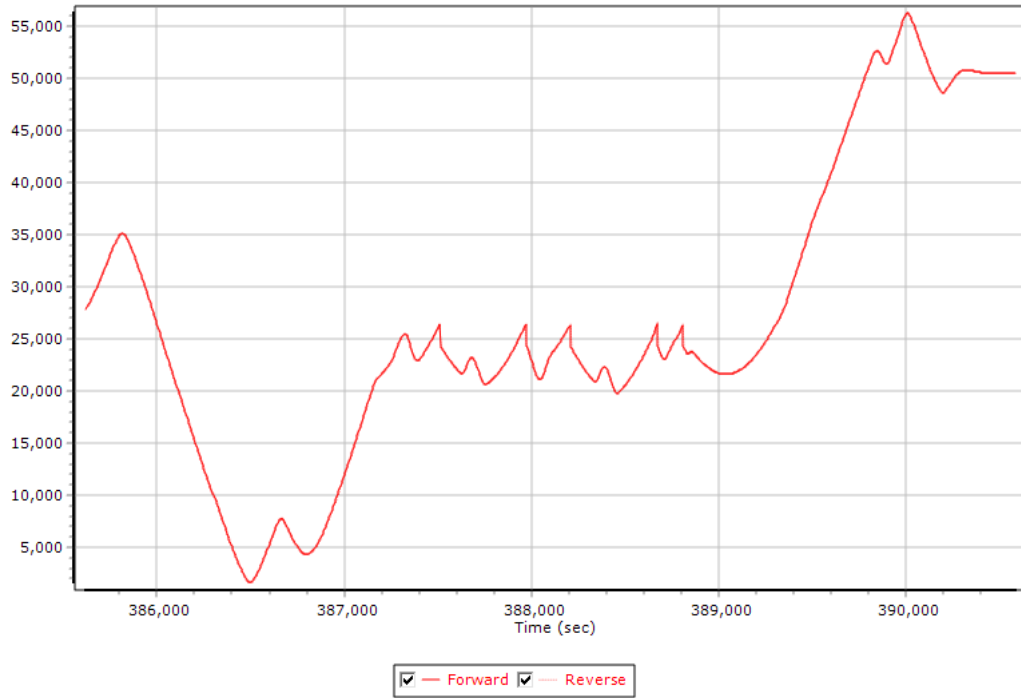
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



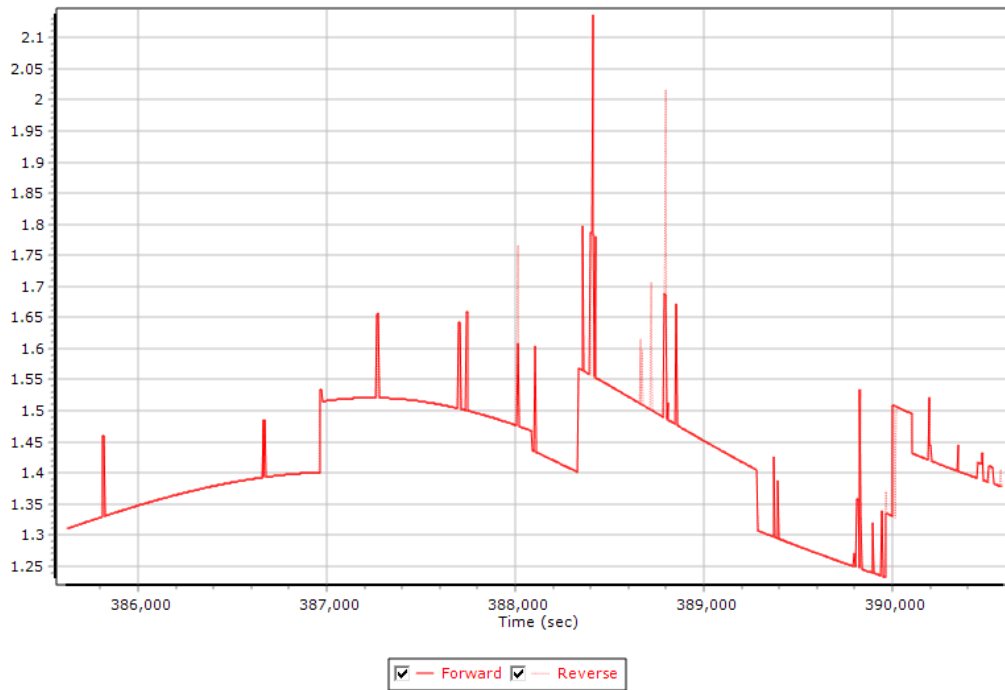


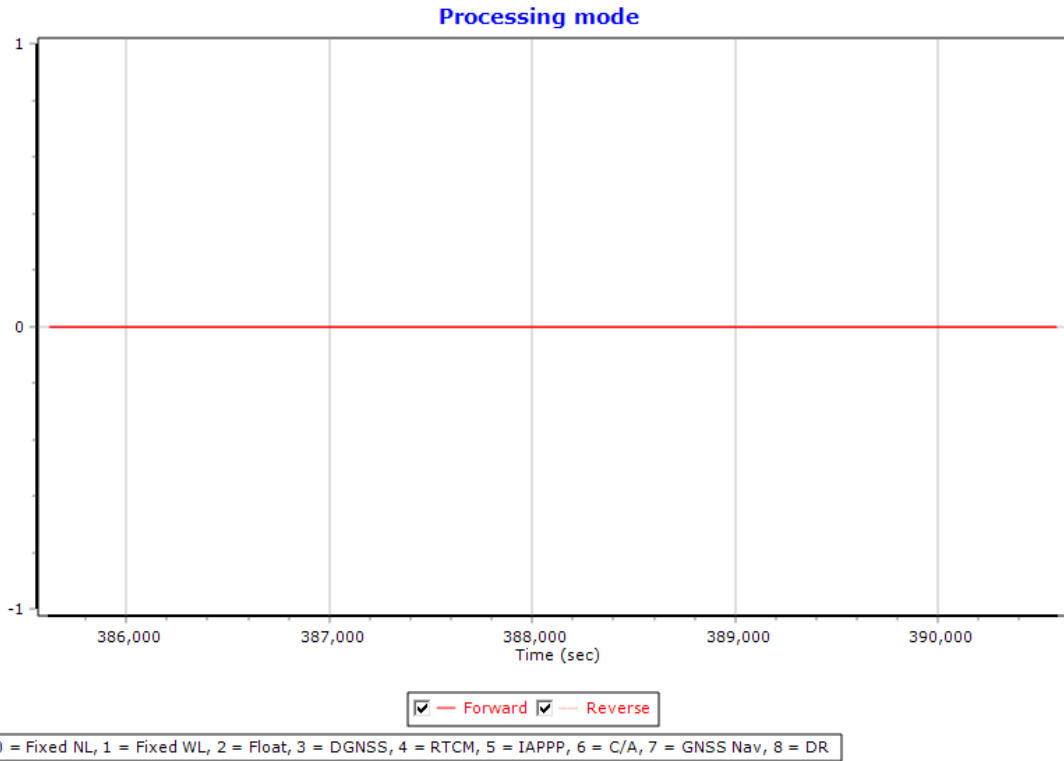


Baseline Length (m)

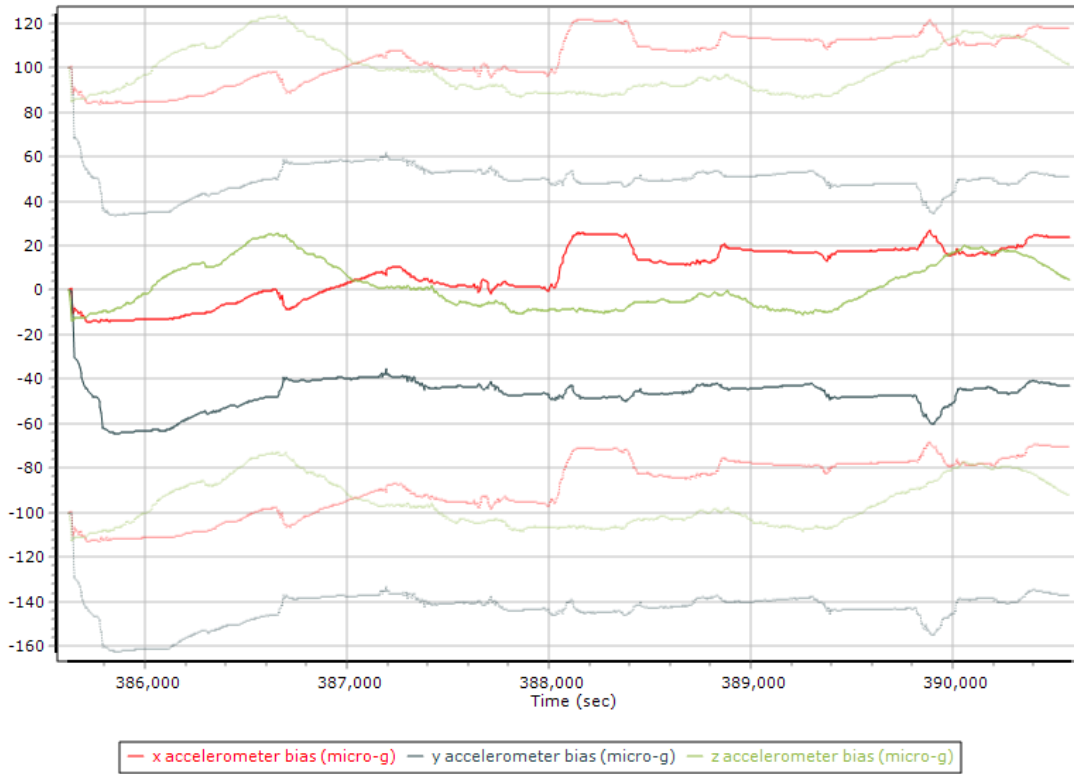


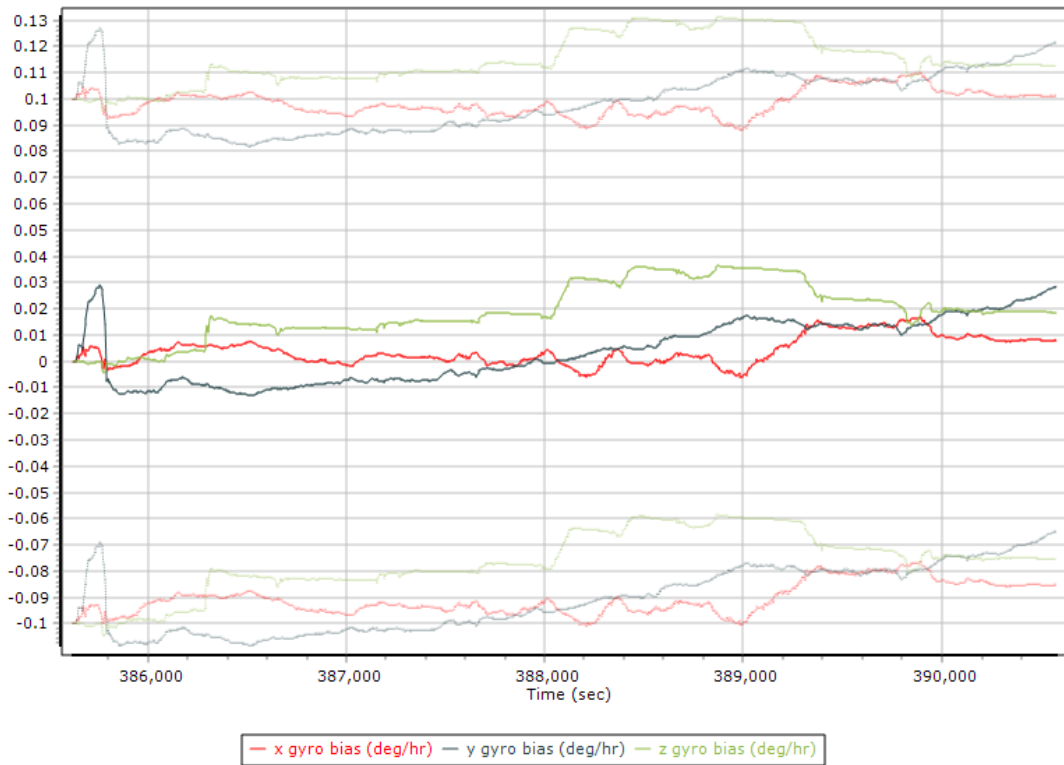
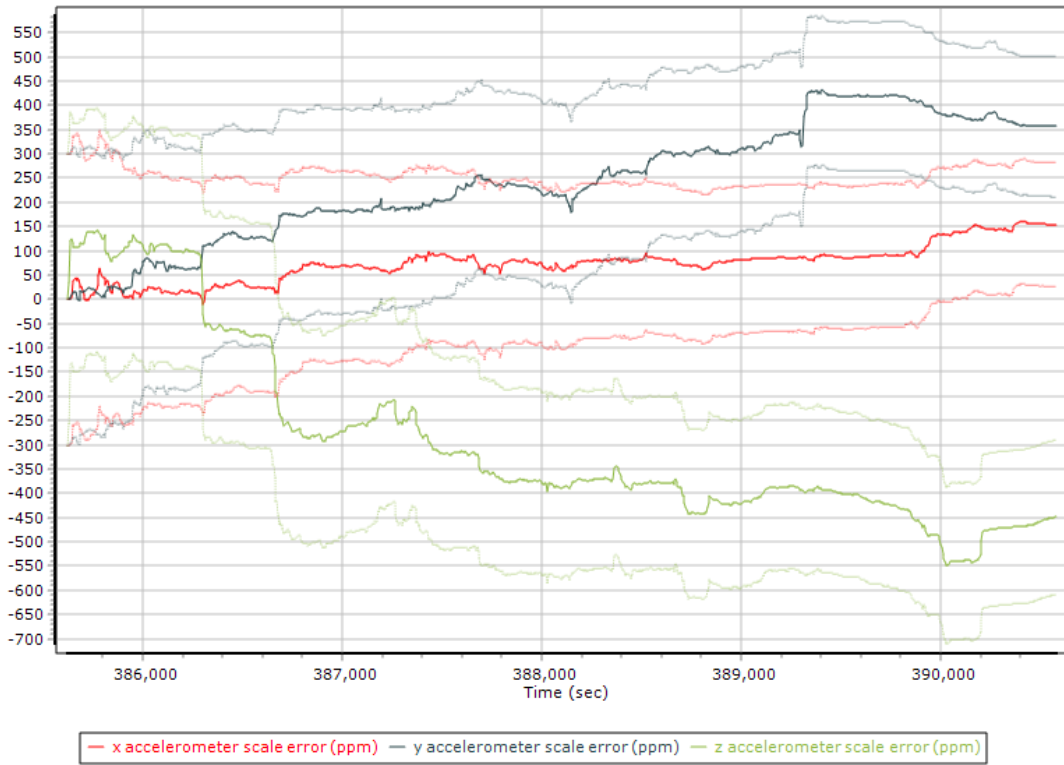
PDOP

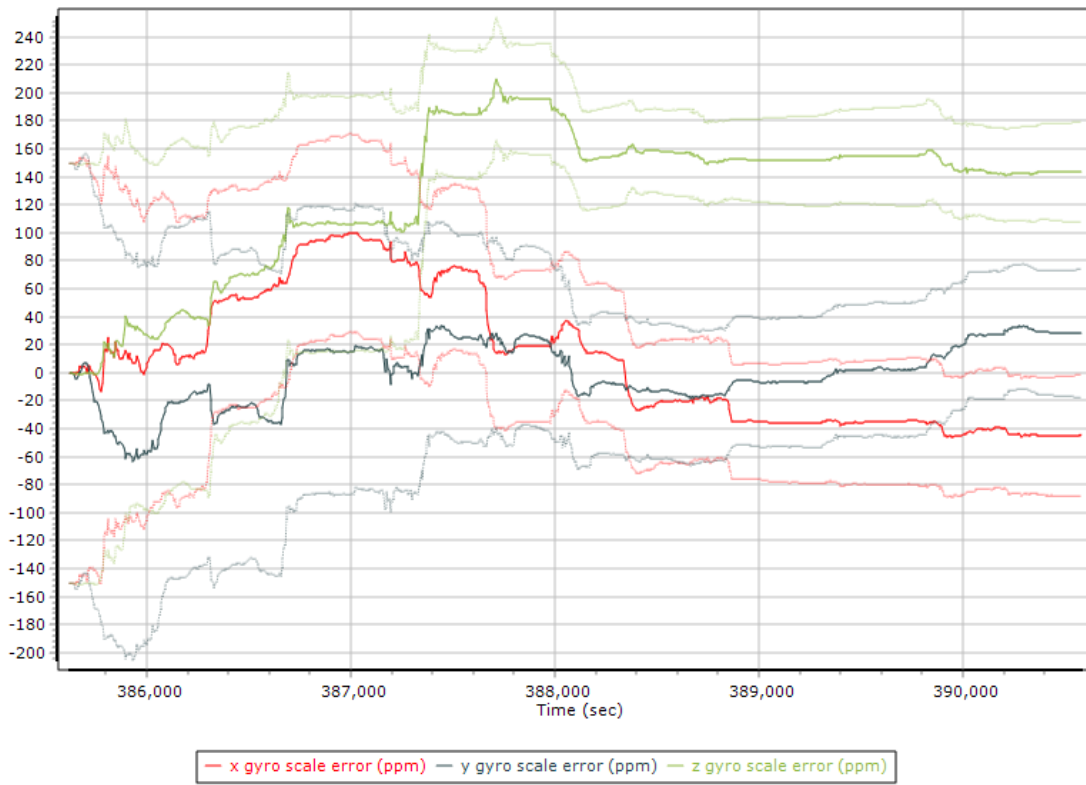




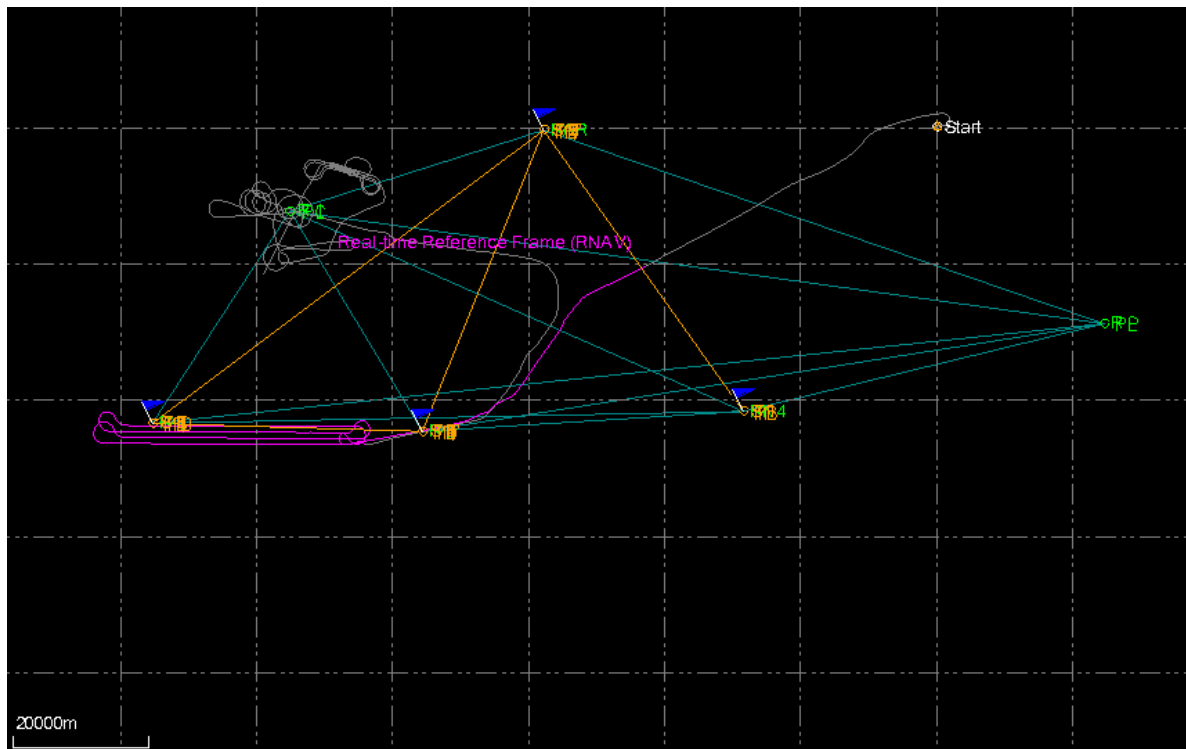
Sensor Errors







RBV18173A



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: -0.034 m
Y: -0.010 m
Z: -0.352 m

Stabilized Mount to IMU Mounting Angles

X: 0.000 deg
Y: 0.000 deg
Z: 0.000 deg

Stabilized Mount to Primary GNSS Lever Arm

X: -0.037 m
Y: 0.007 m
Z: -0.985 m

Aircraft to Stabilized Mount Mounting Angles

X: 0.000 deg
Y: 0.000 deg
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
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

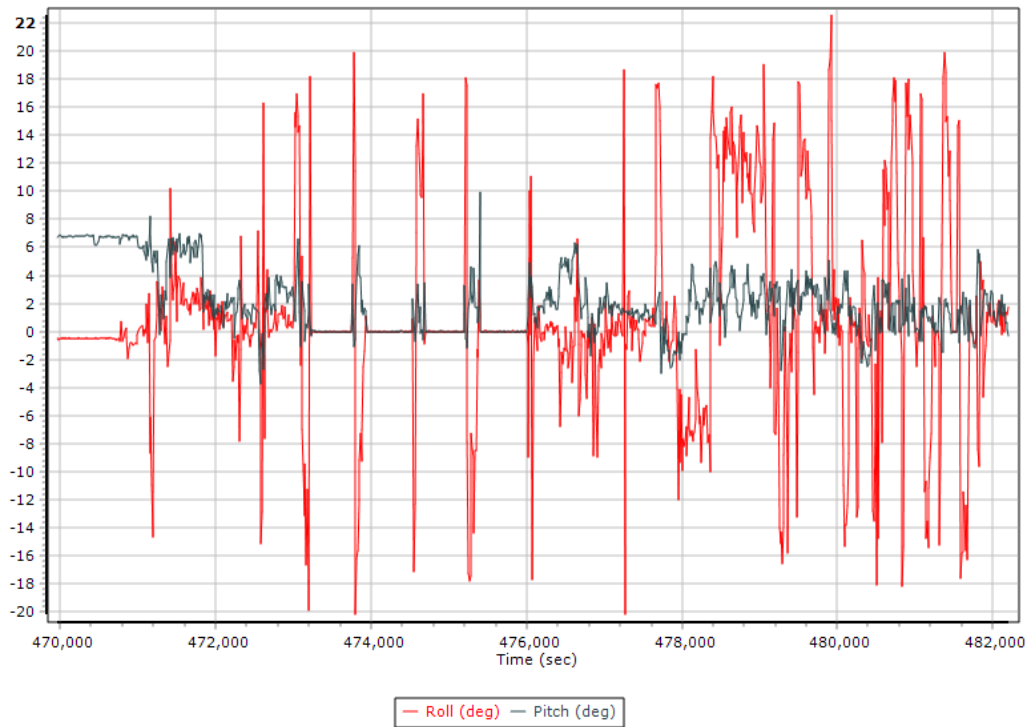
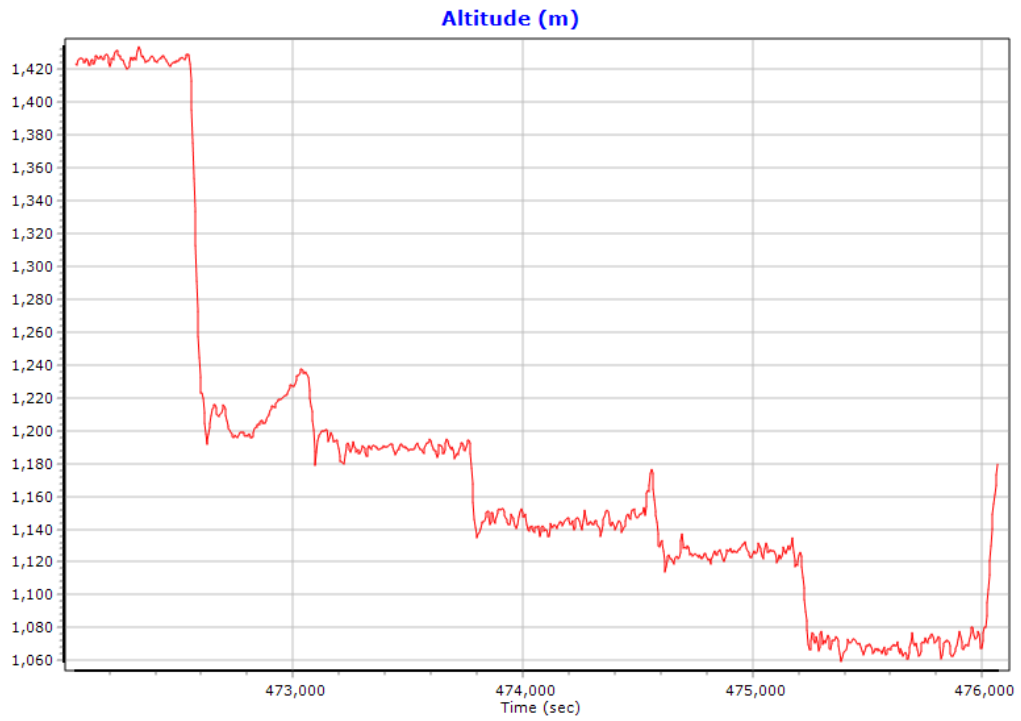
Timing

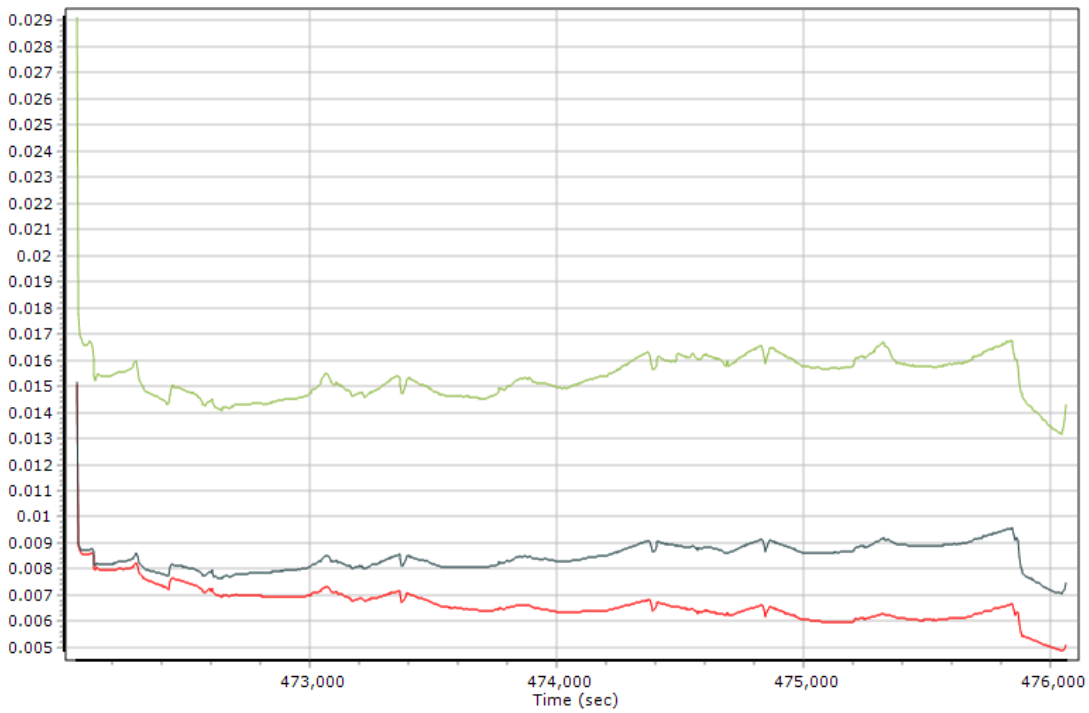
Start: 472057.018
End: 476071.956

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

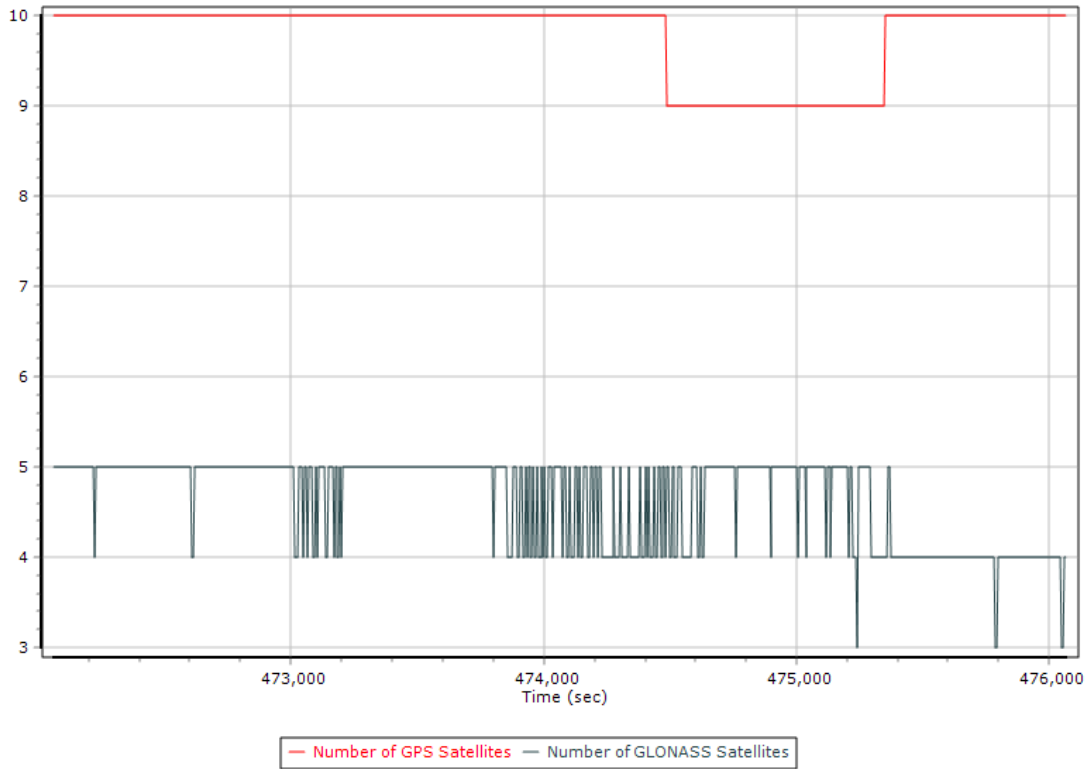




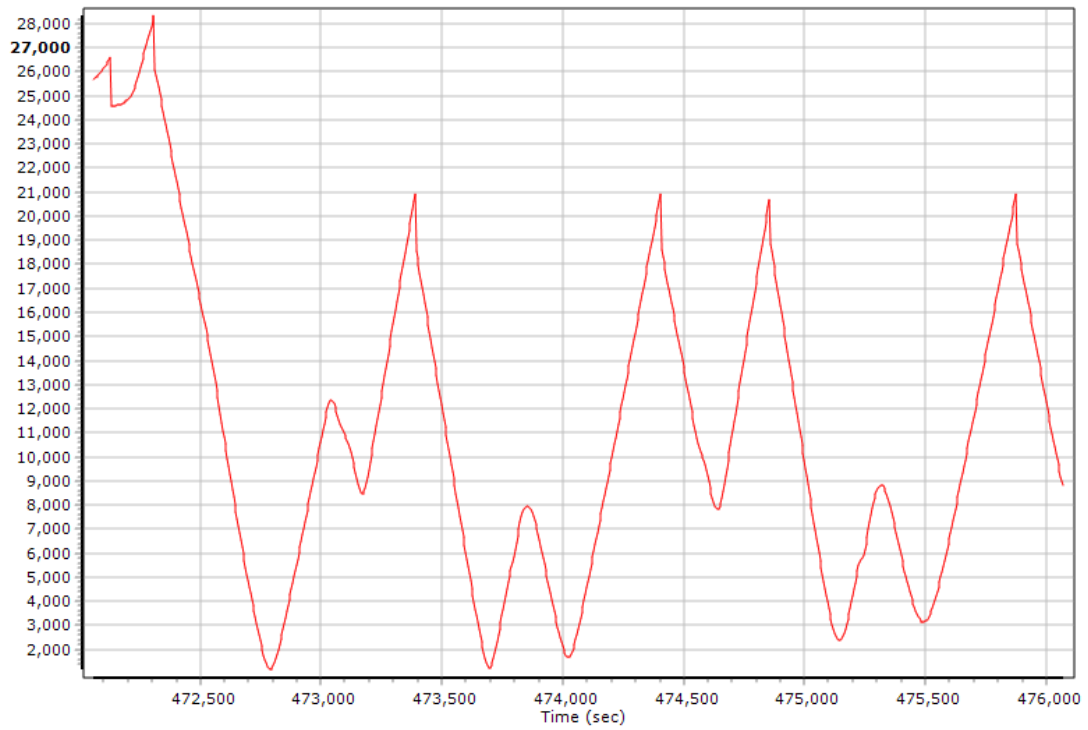
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



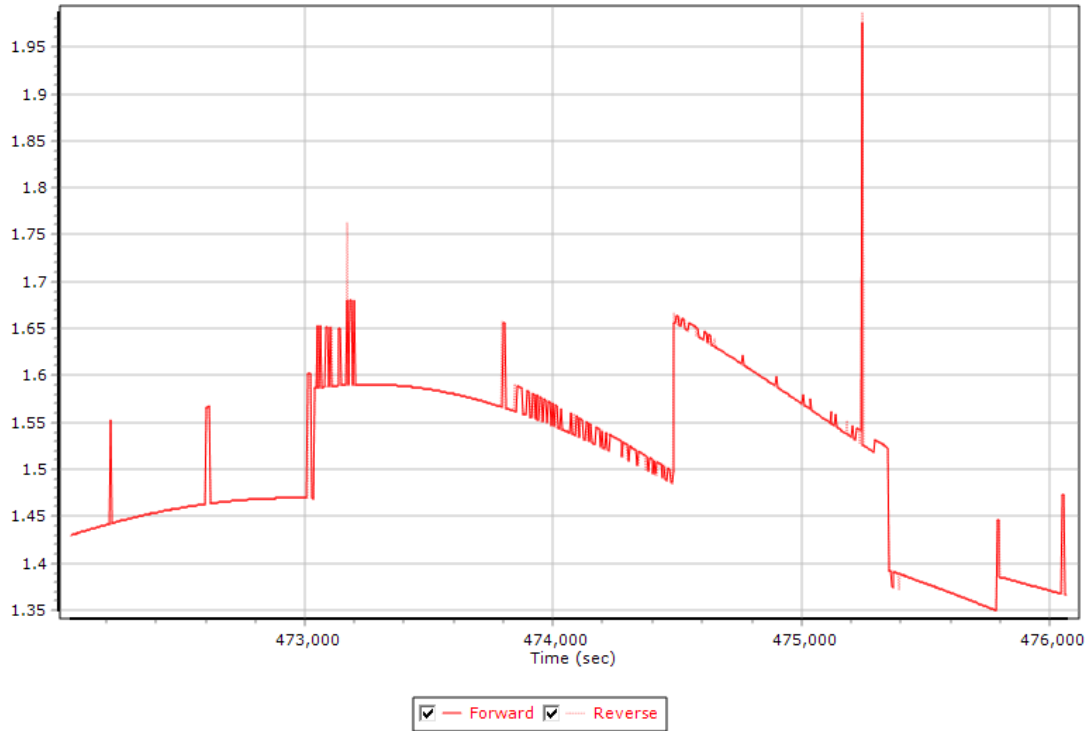
— North (m) — East (m) — Down (m) — DR mode



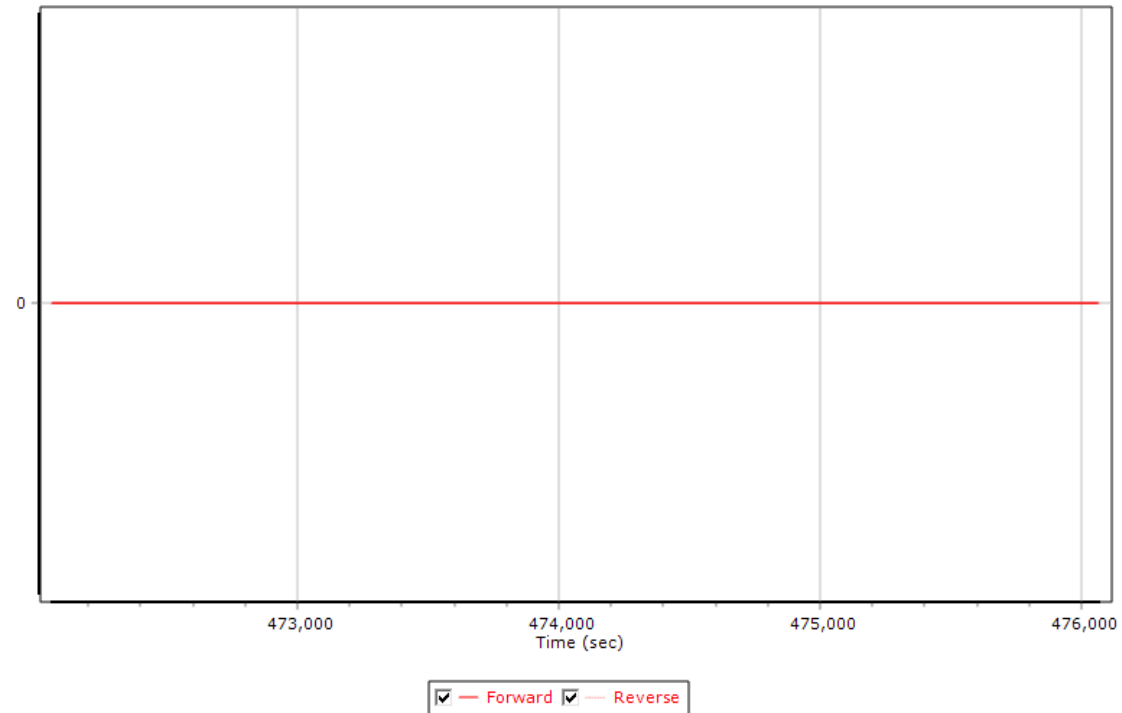
Baseline Length(m)



PDOP

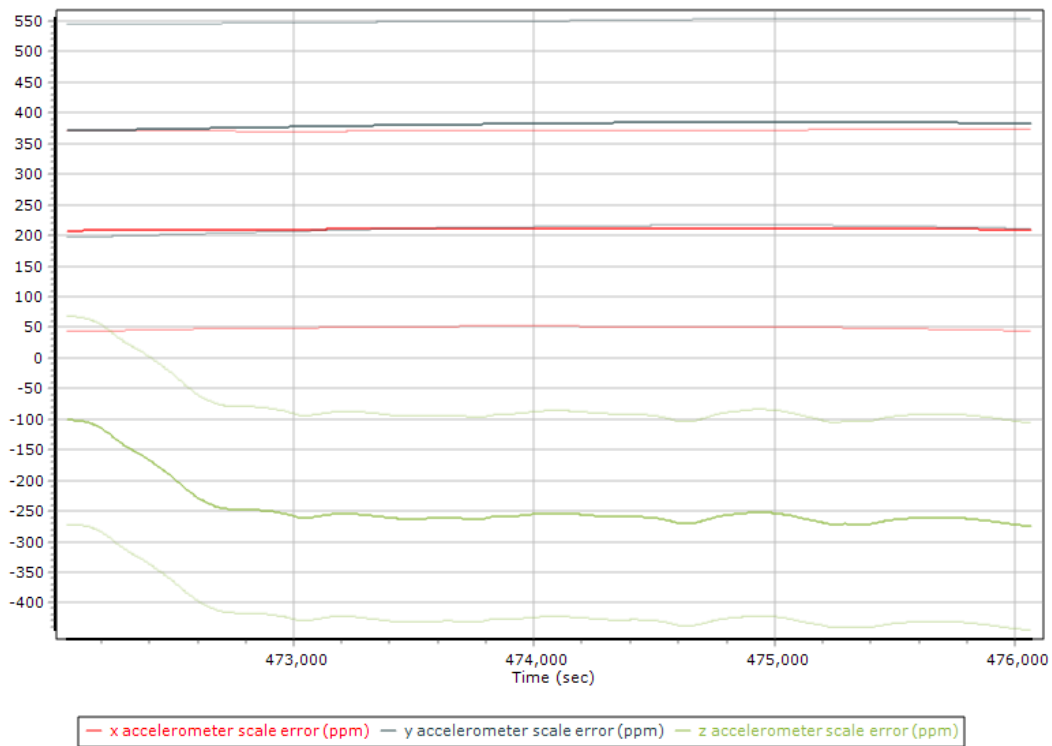
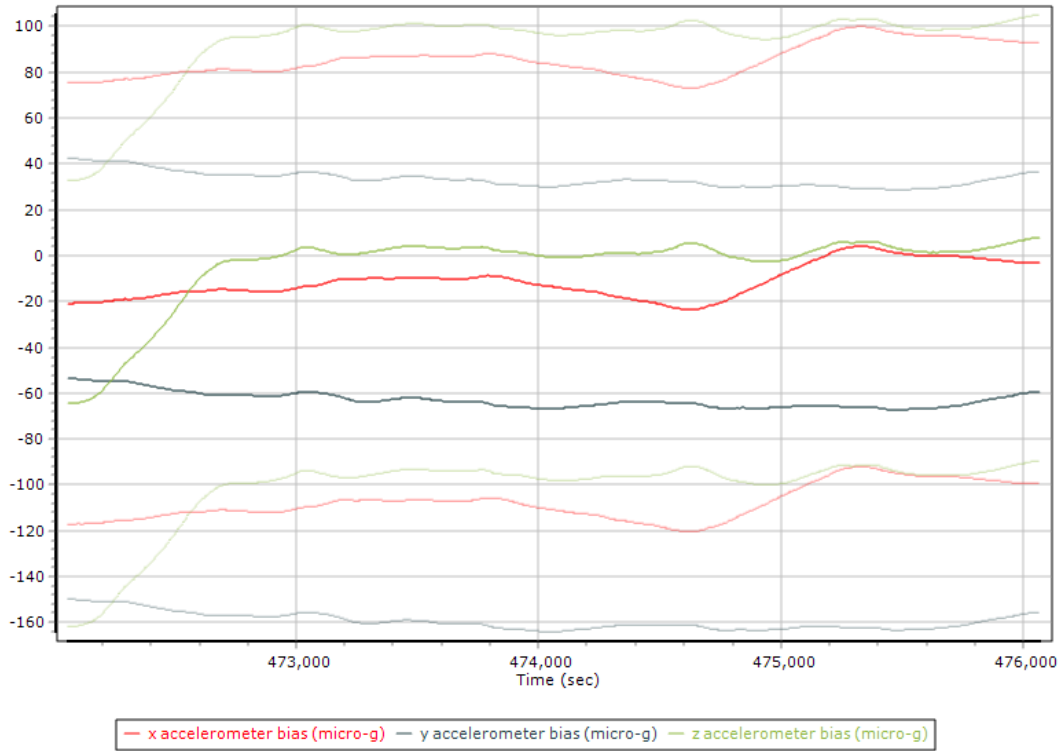


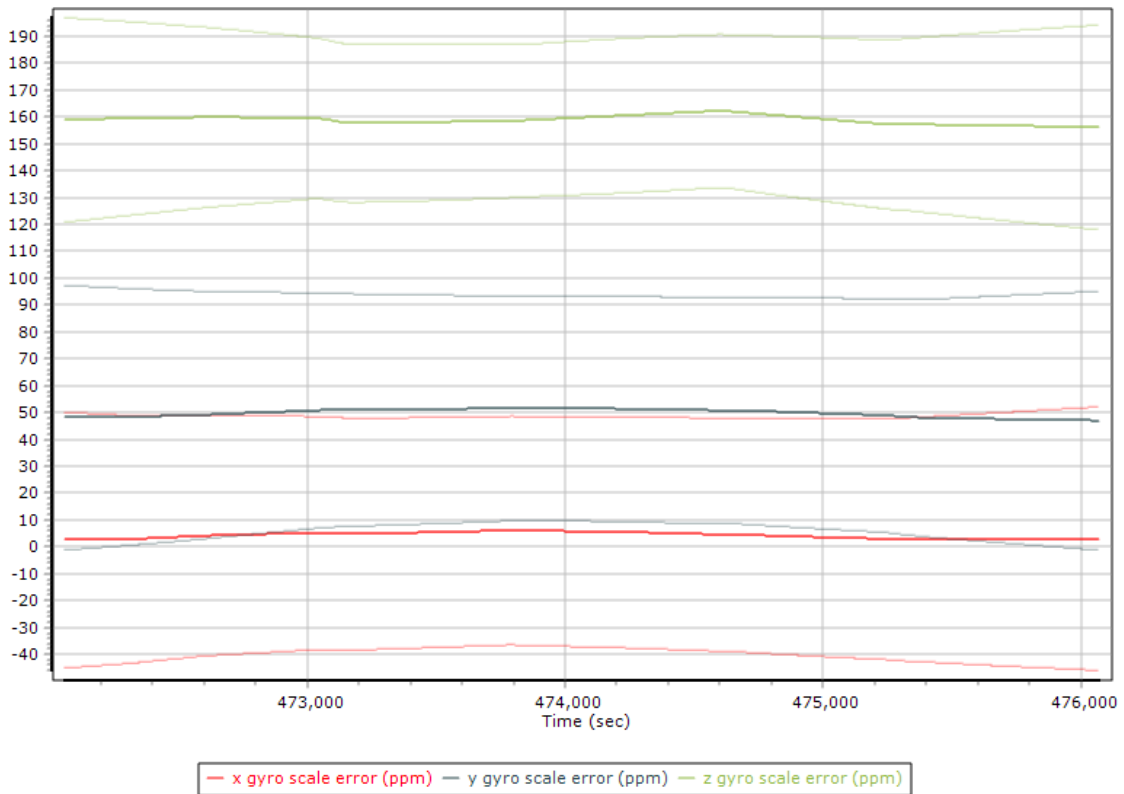
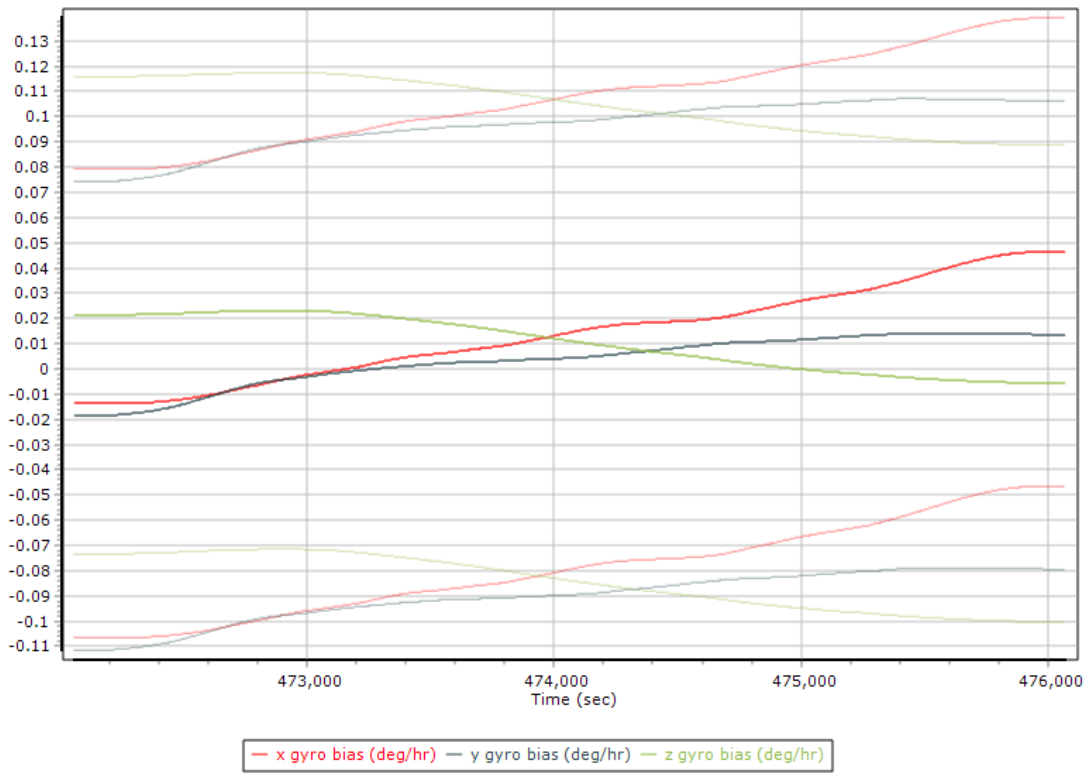
Processing Mode



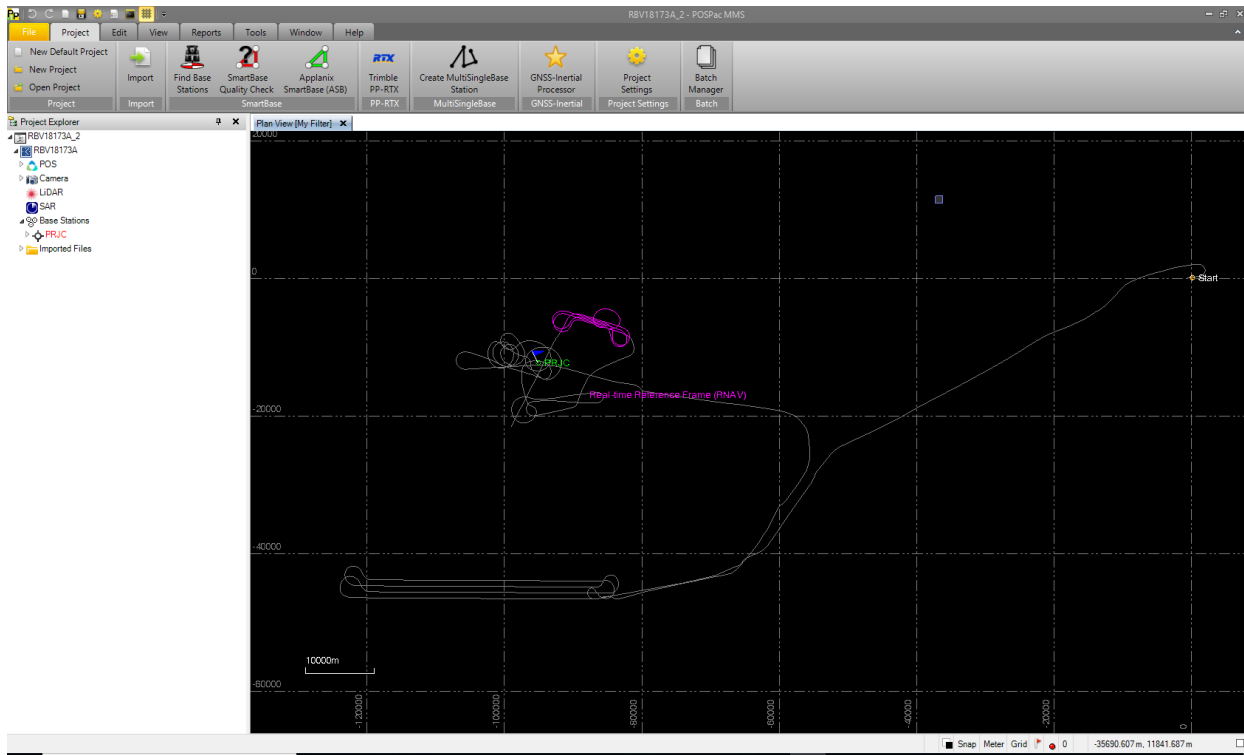
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





RBV18173A2



Project Settings

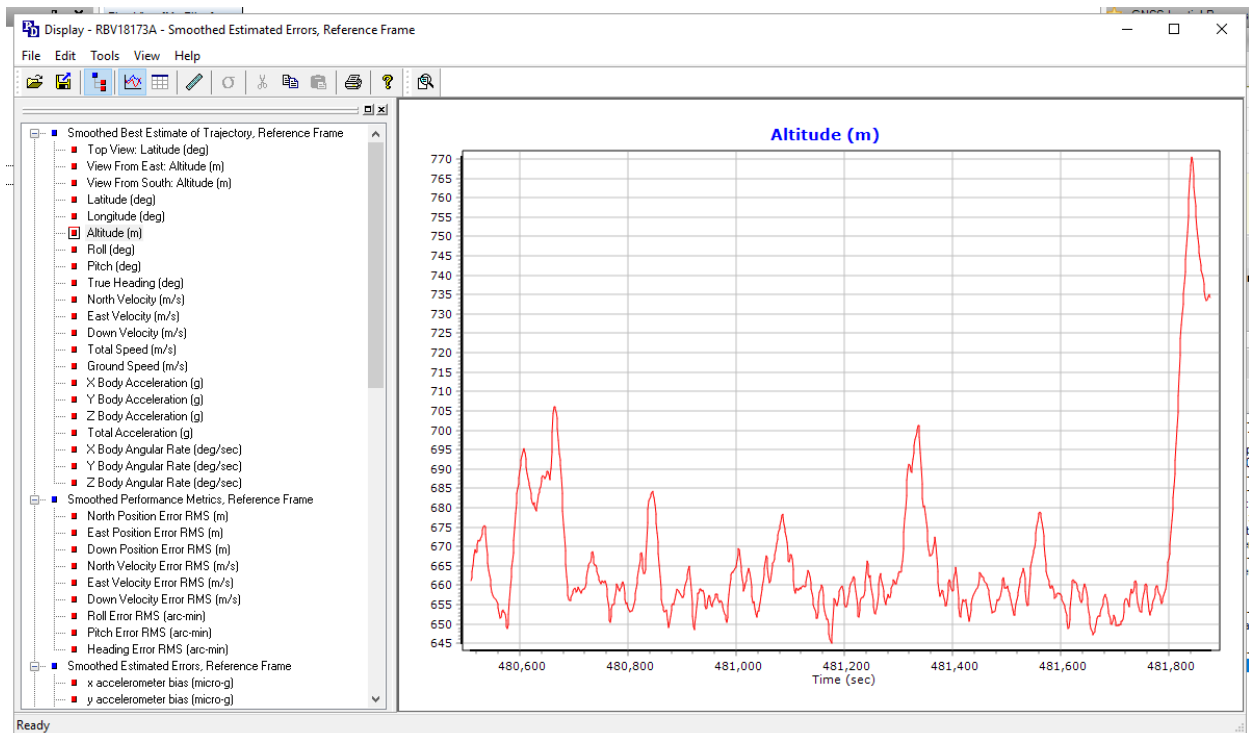
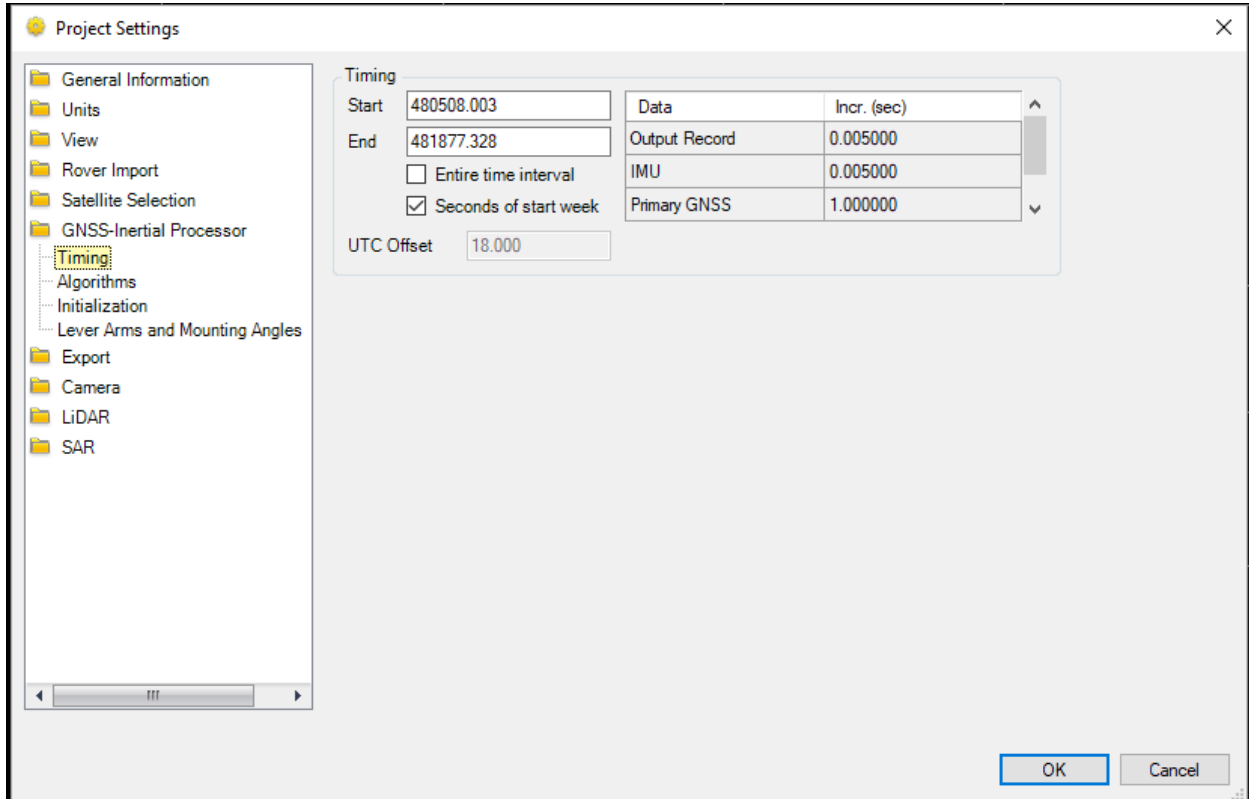
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

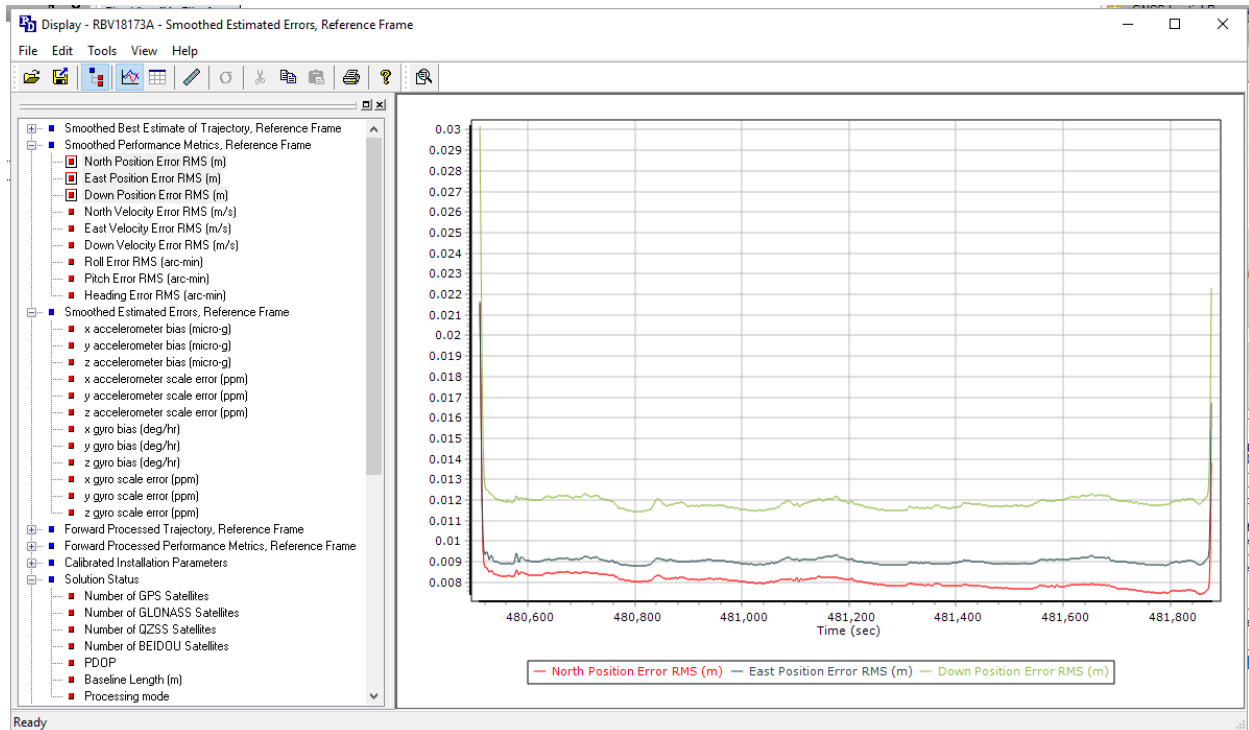
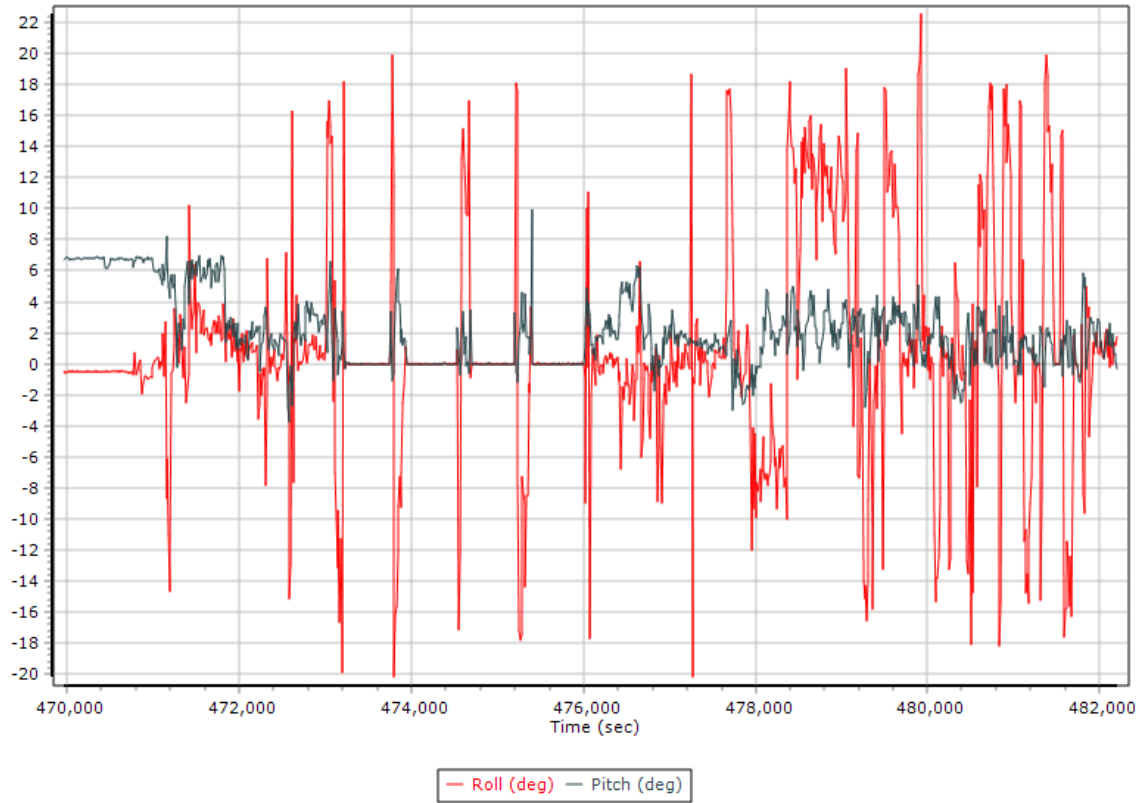
Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.037 m	0.007 m	-0.985 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

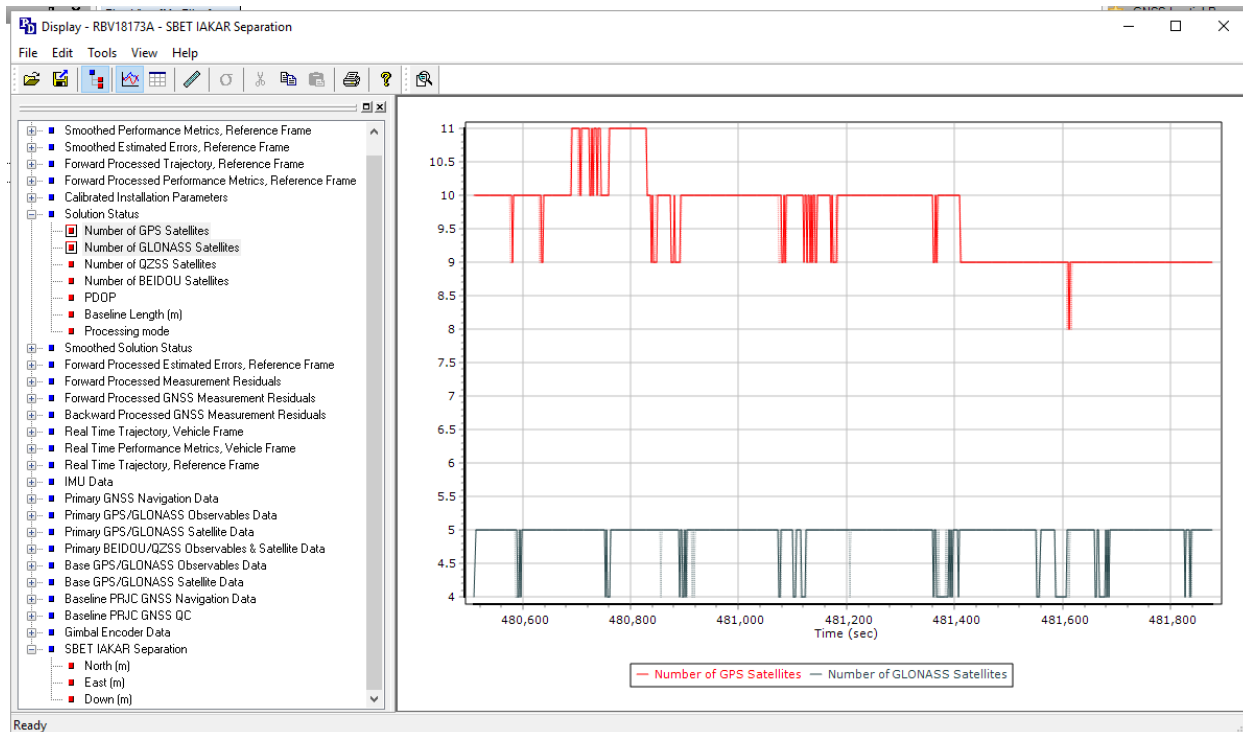
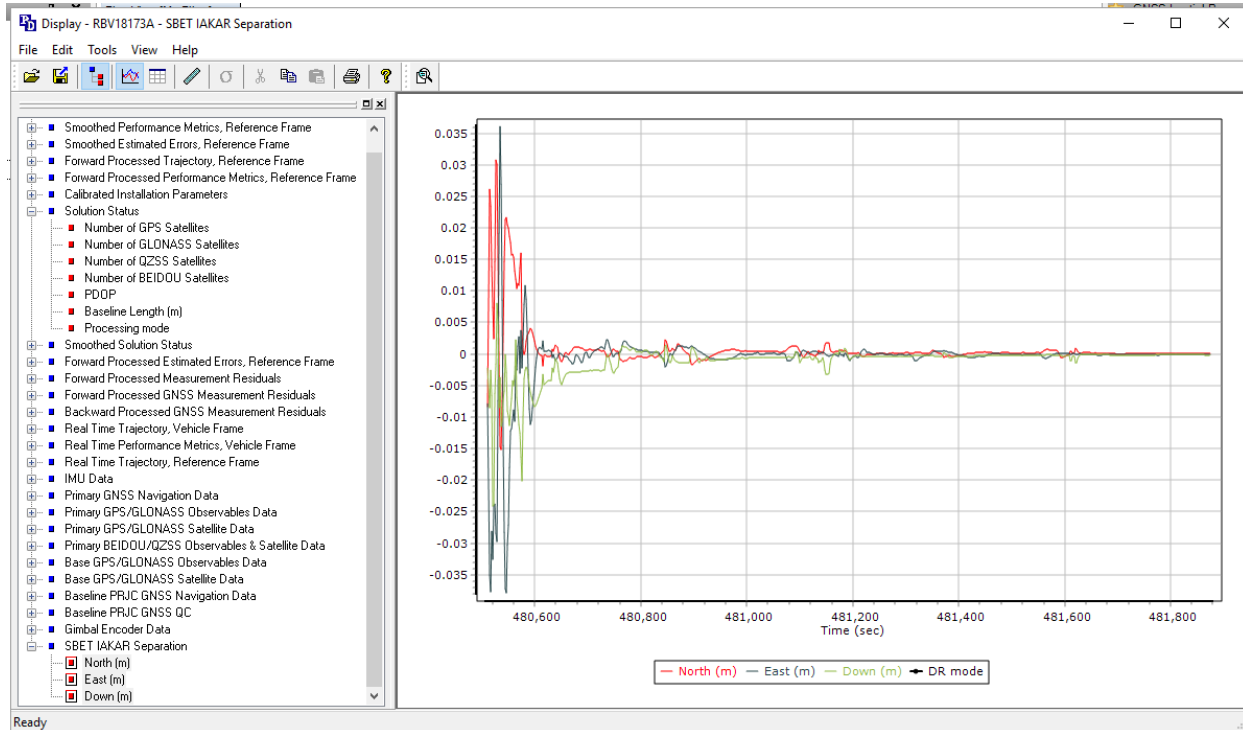
Standard Deviation: <3cm 10cm 50cm 1m 10m

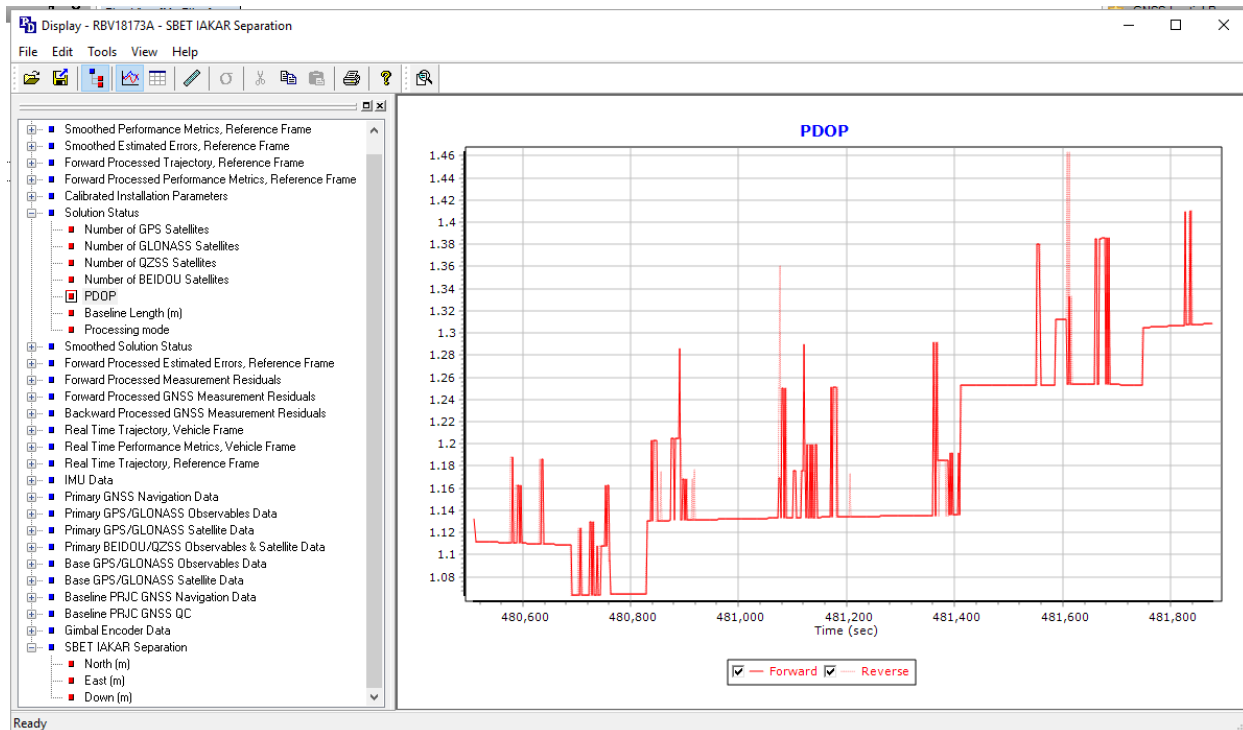
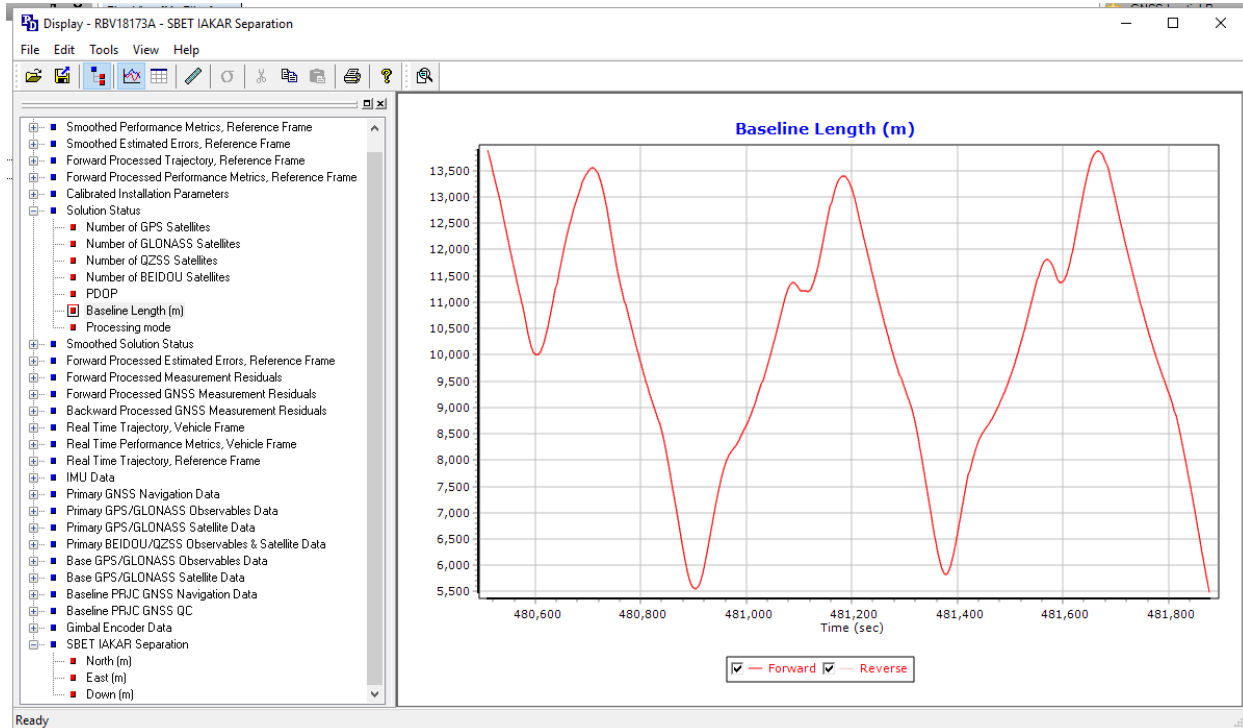
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

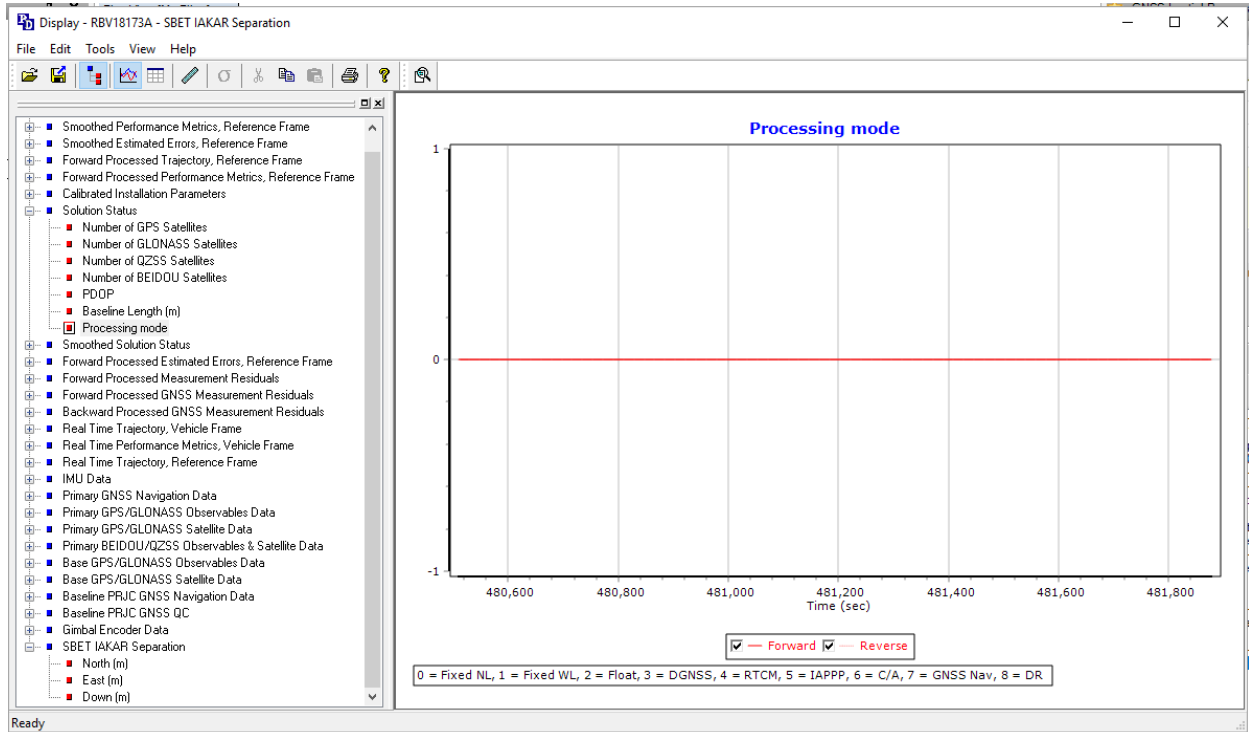
OK Cancel



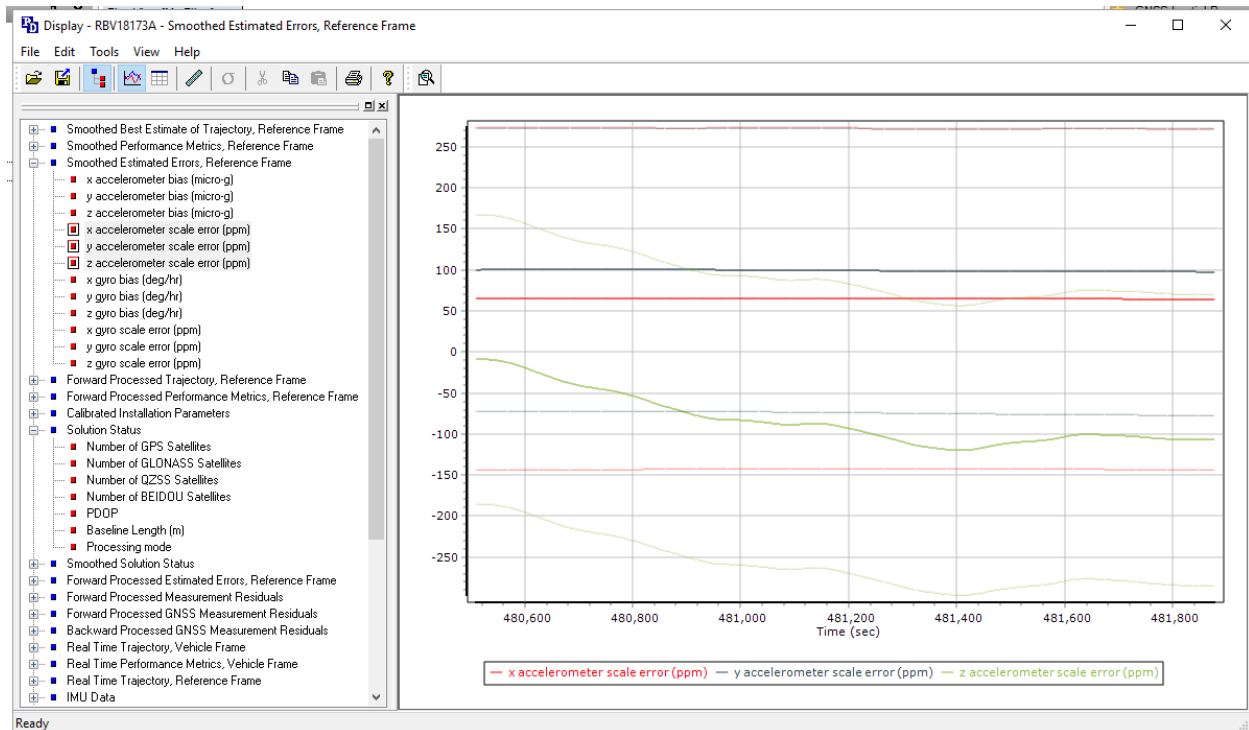
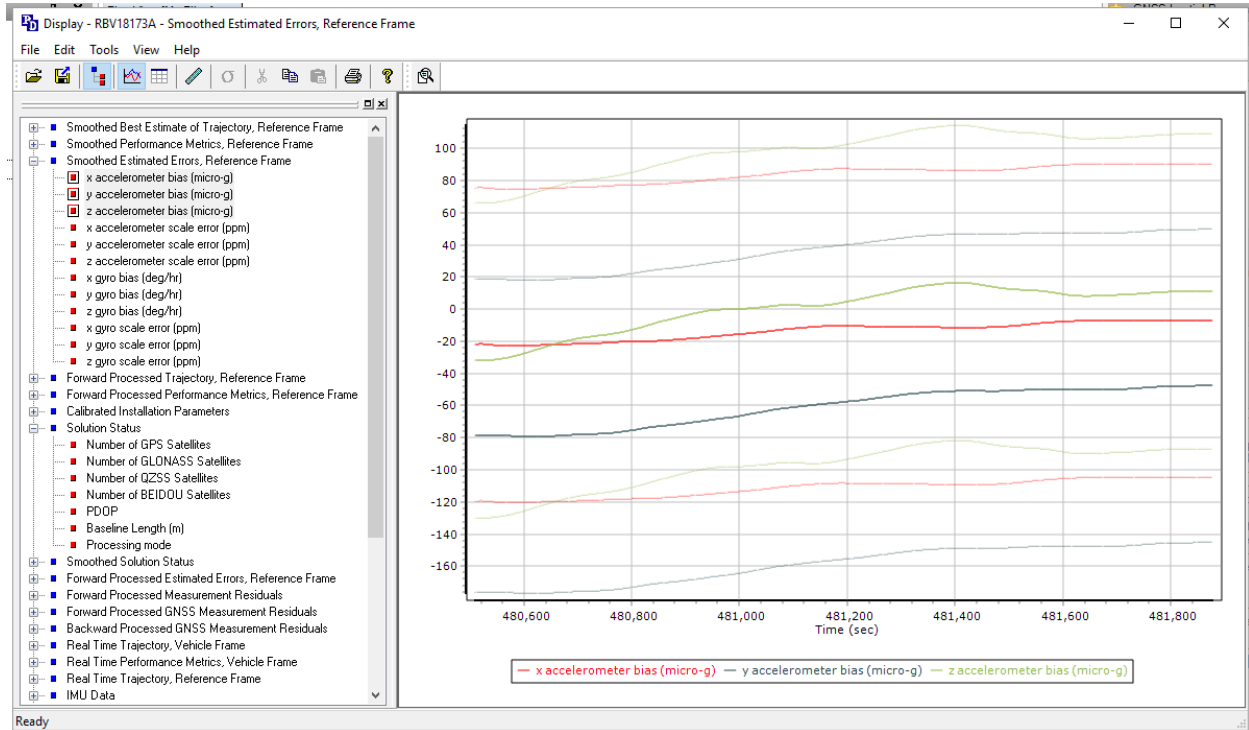


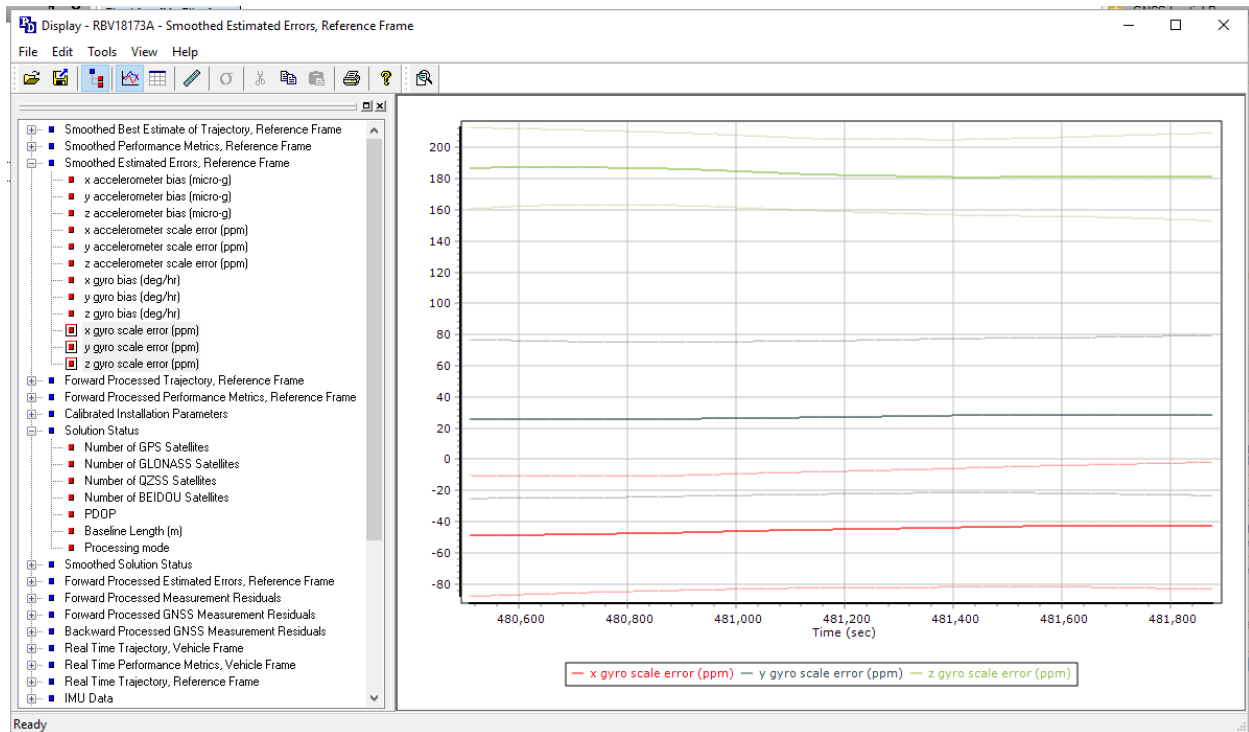
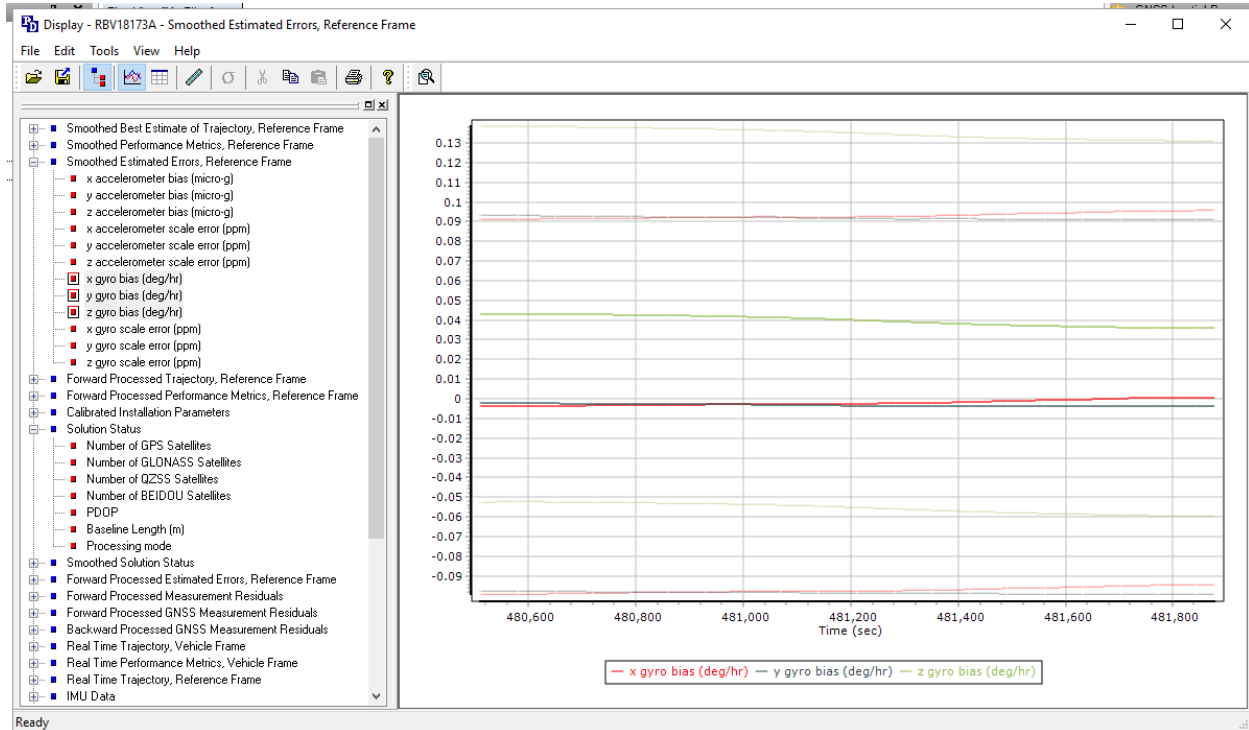




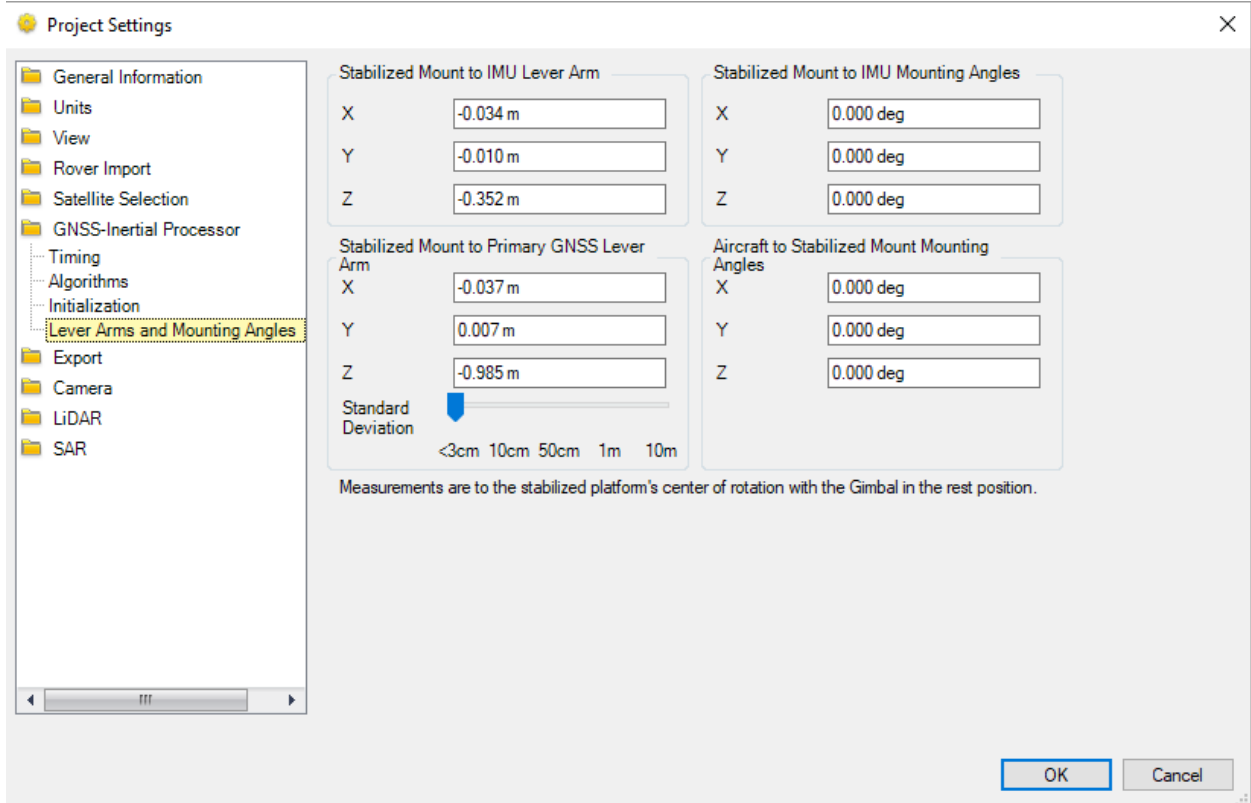
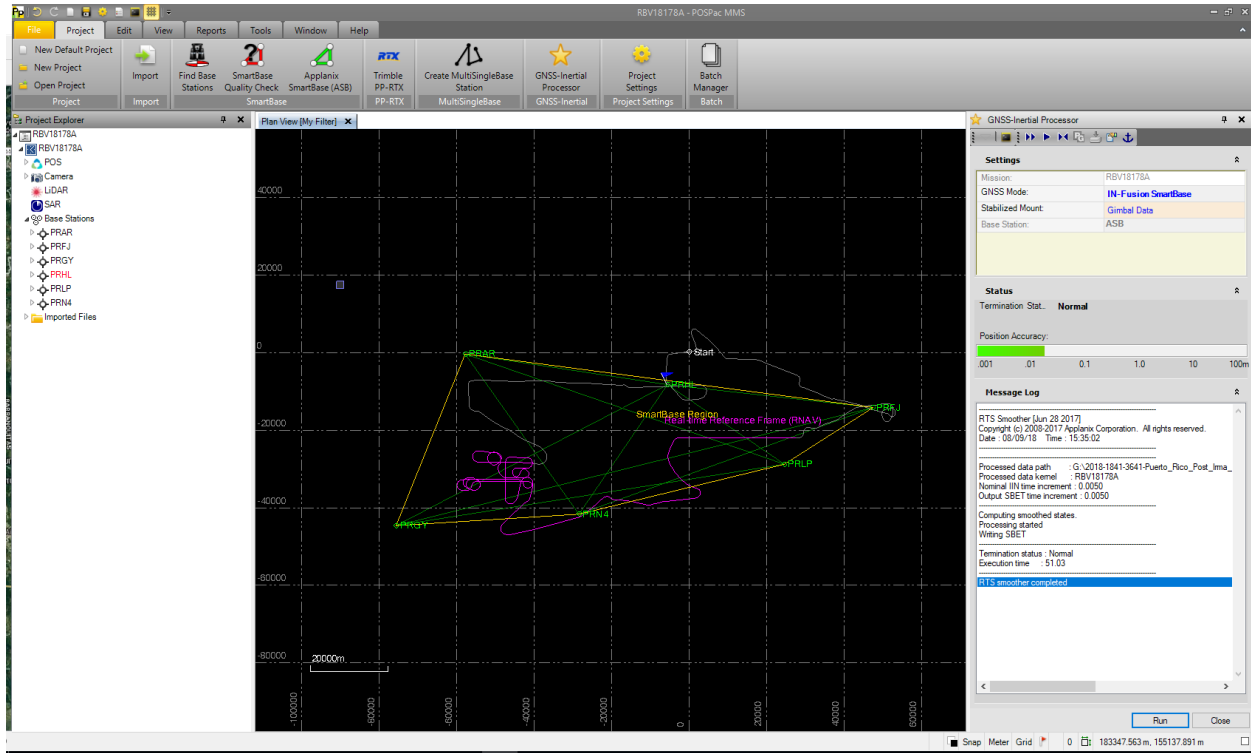


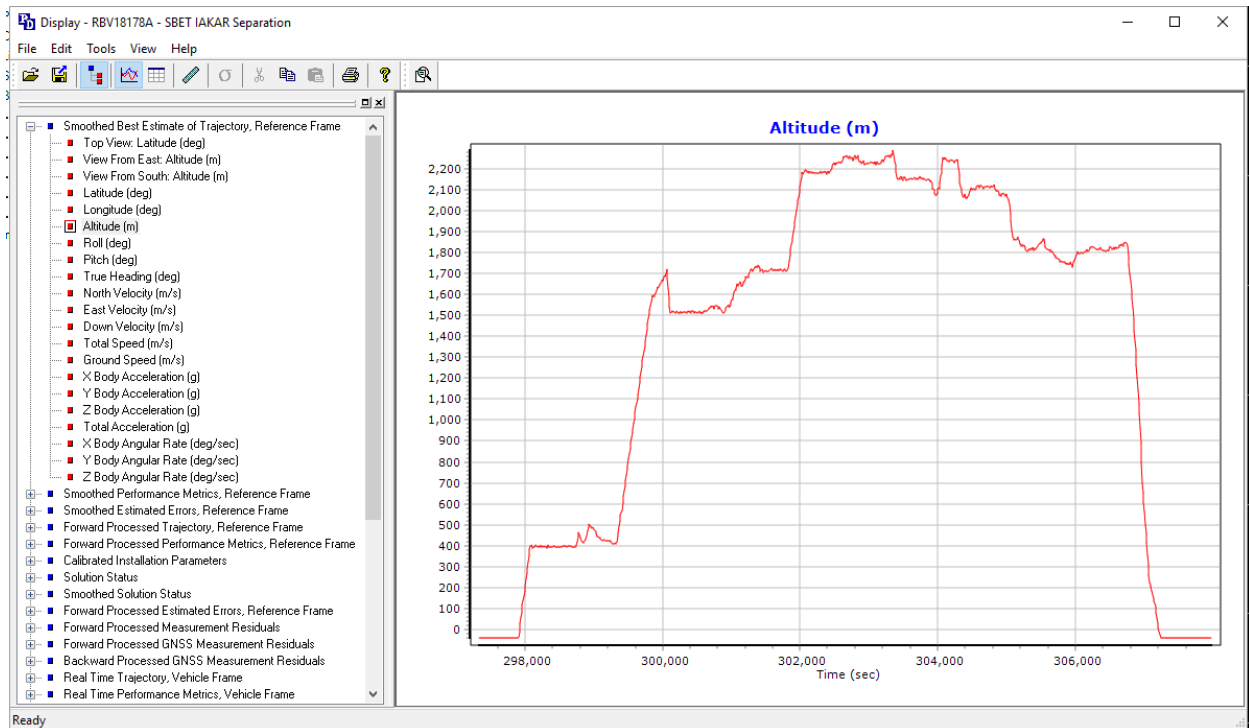
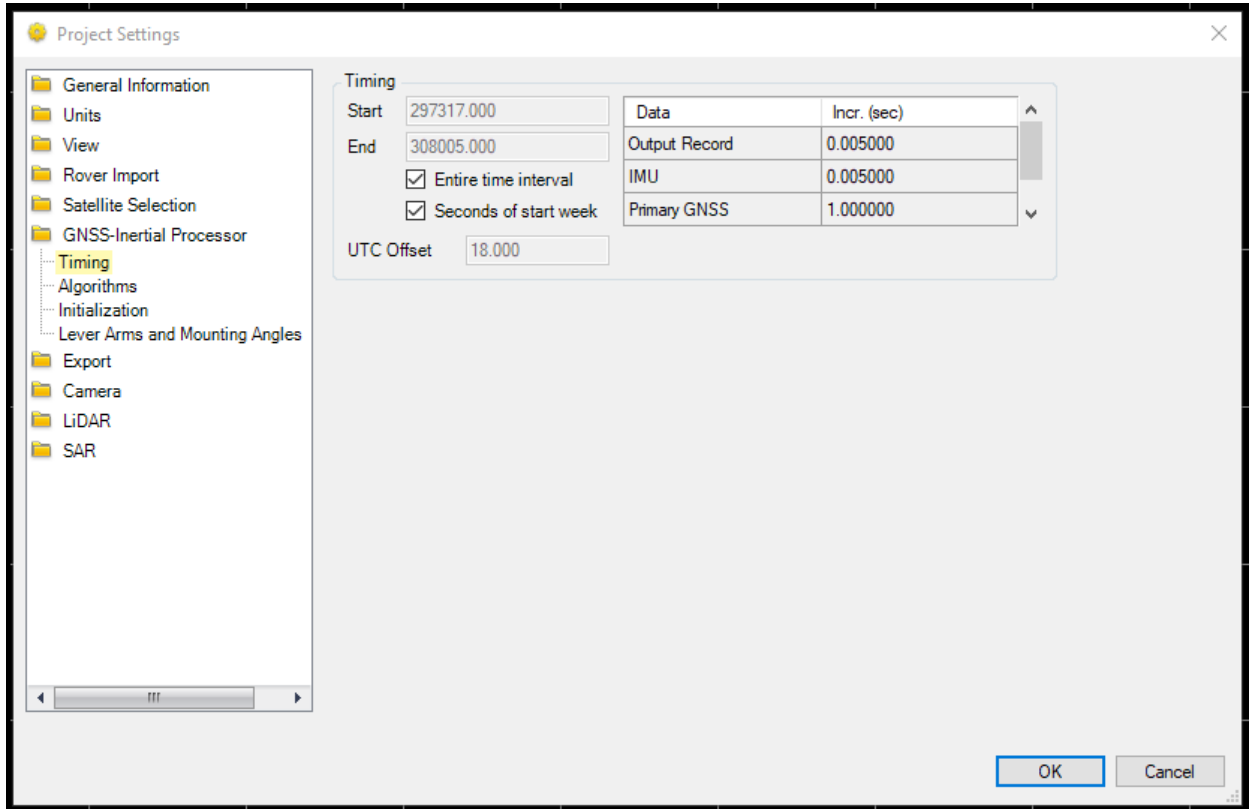
Sensor Errors

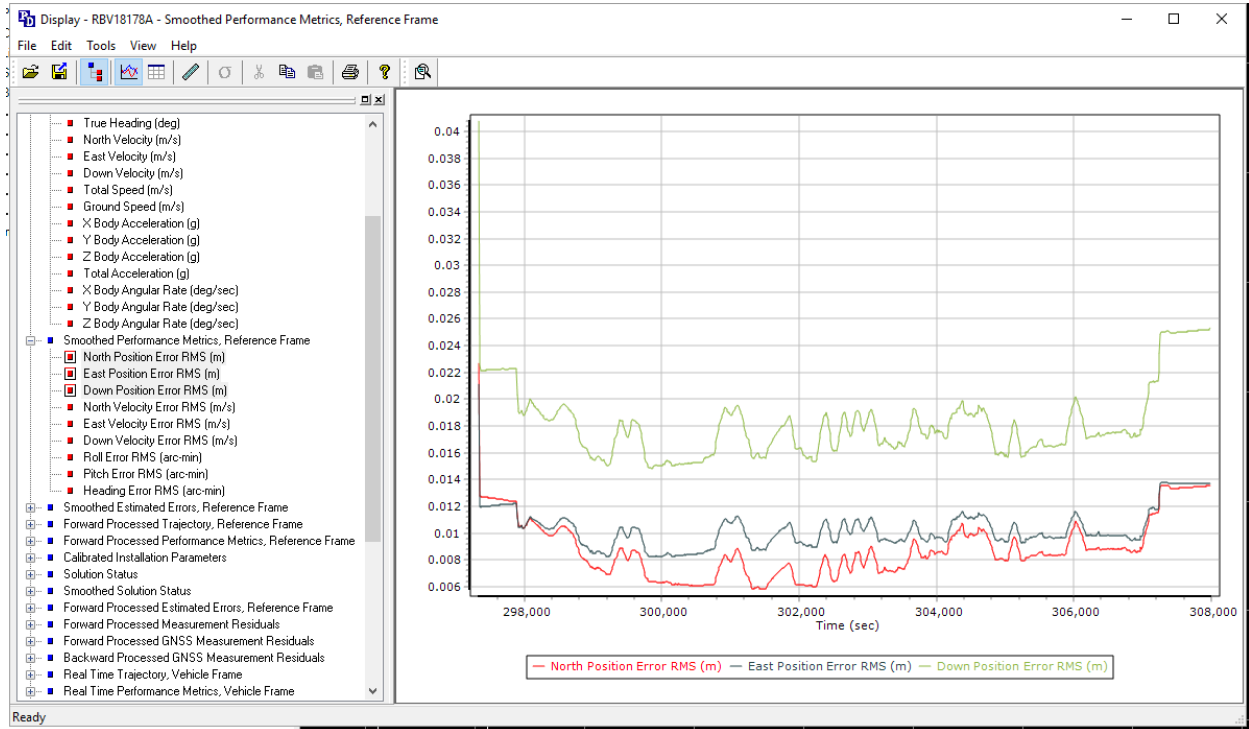
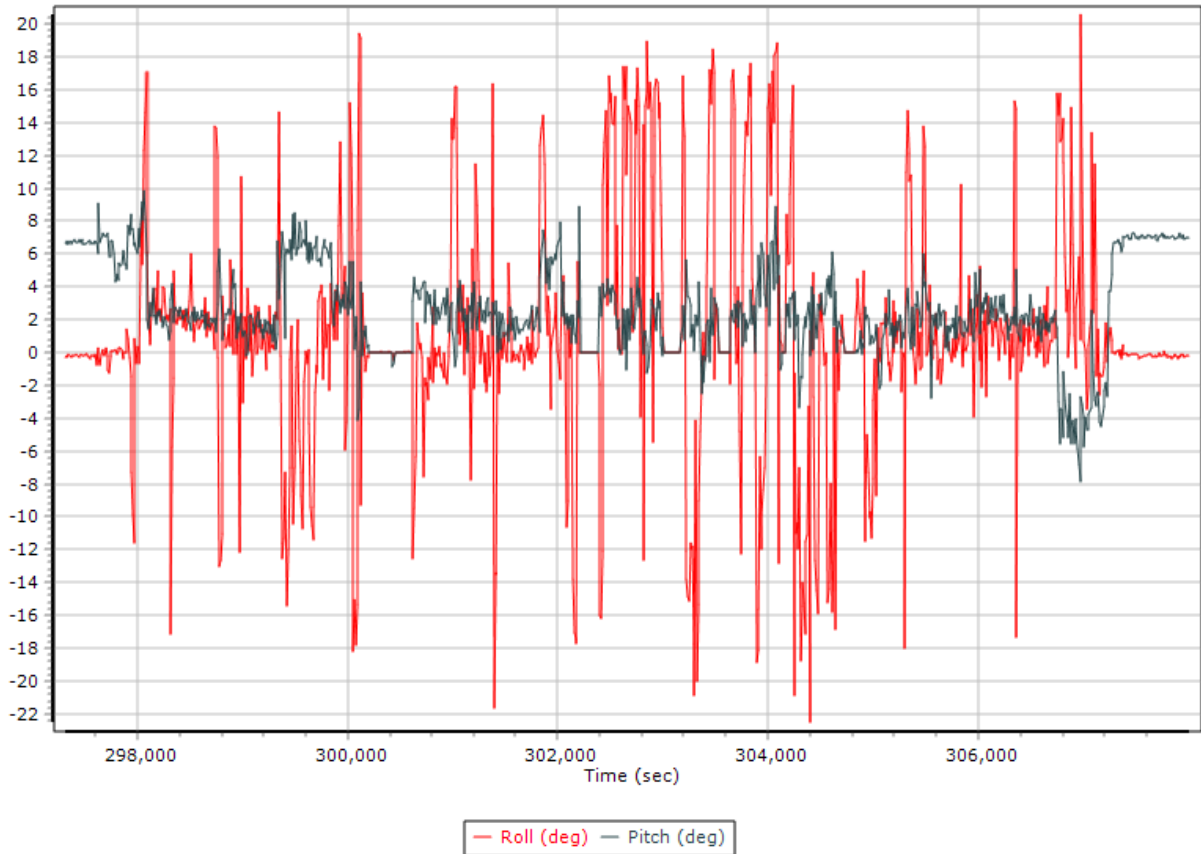


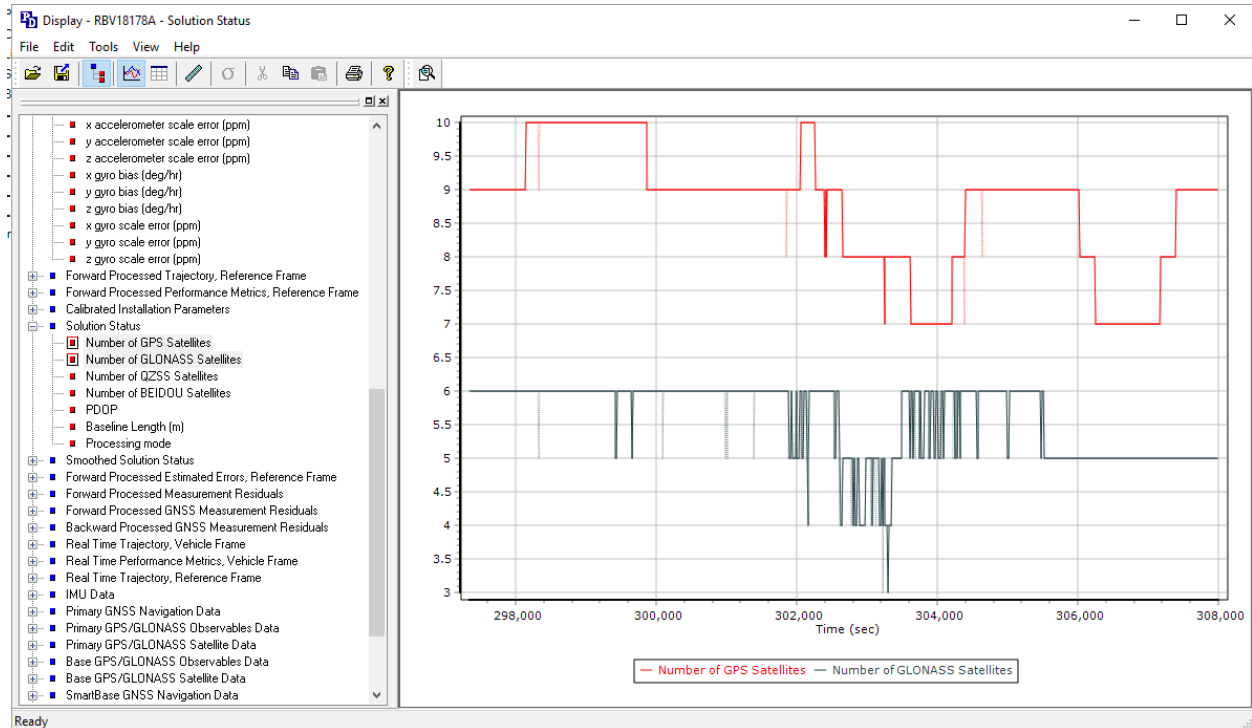
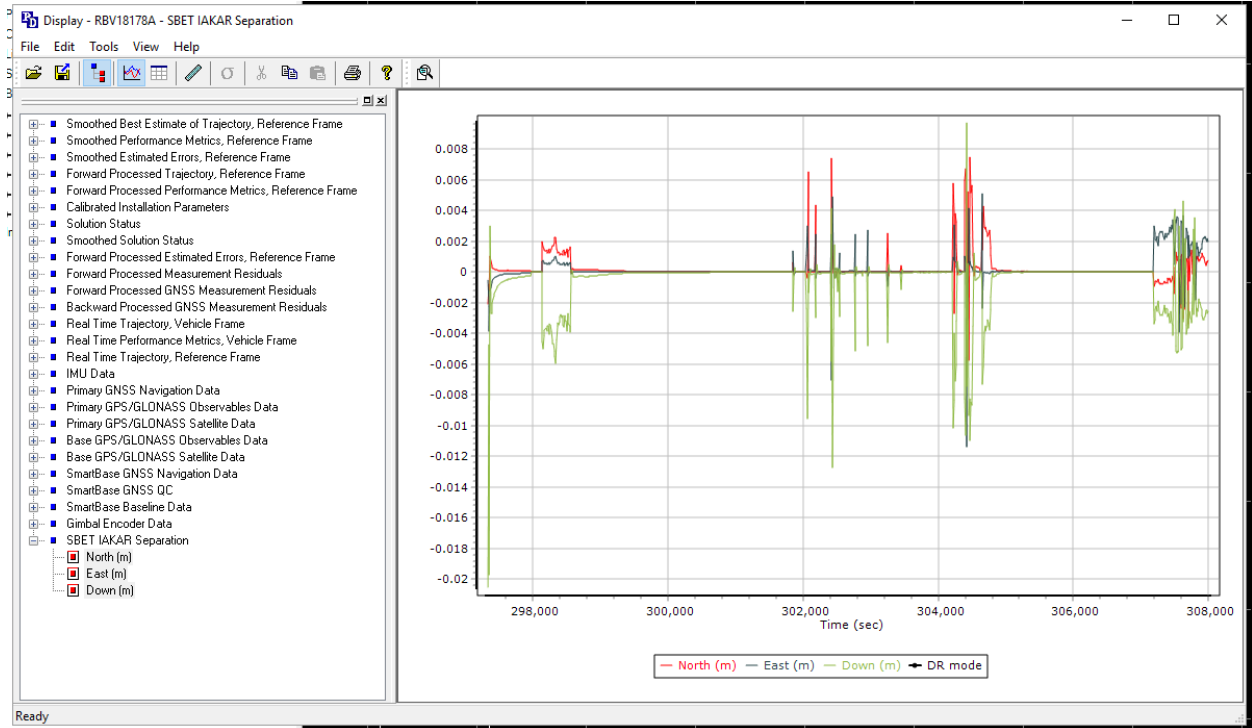


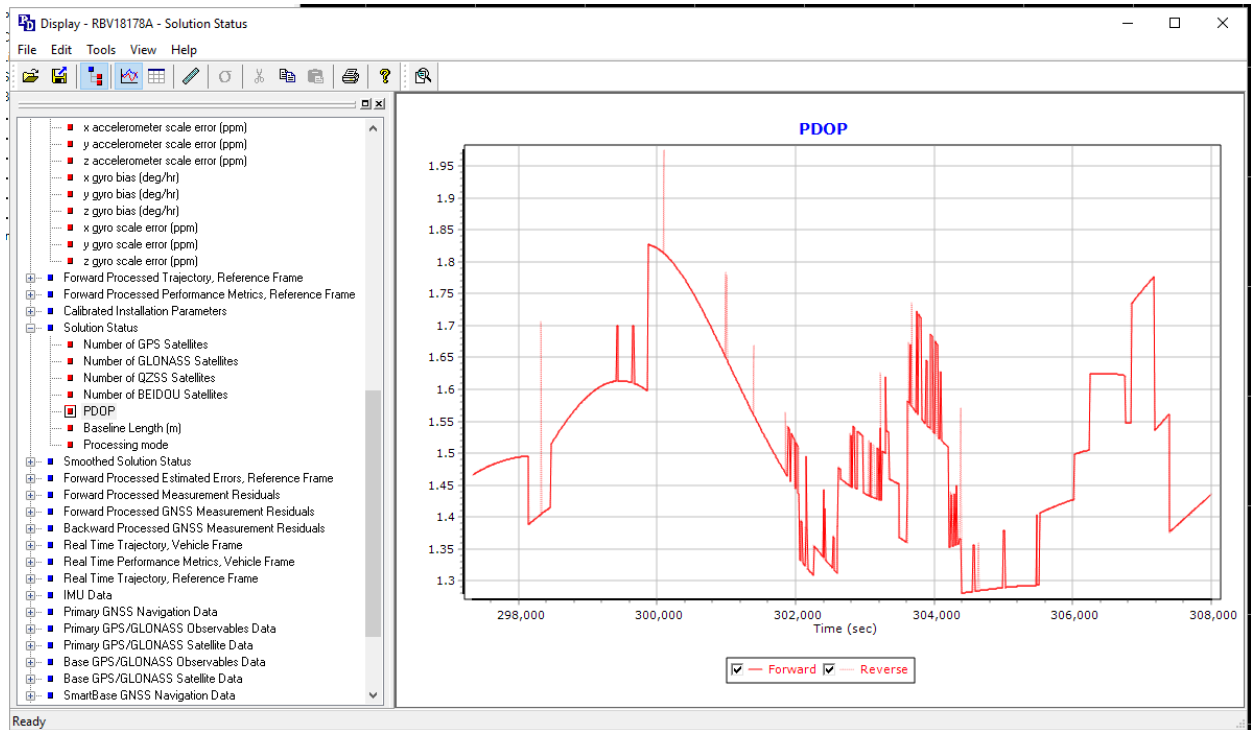
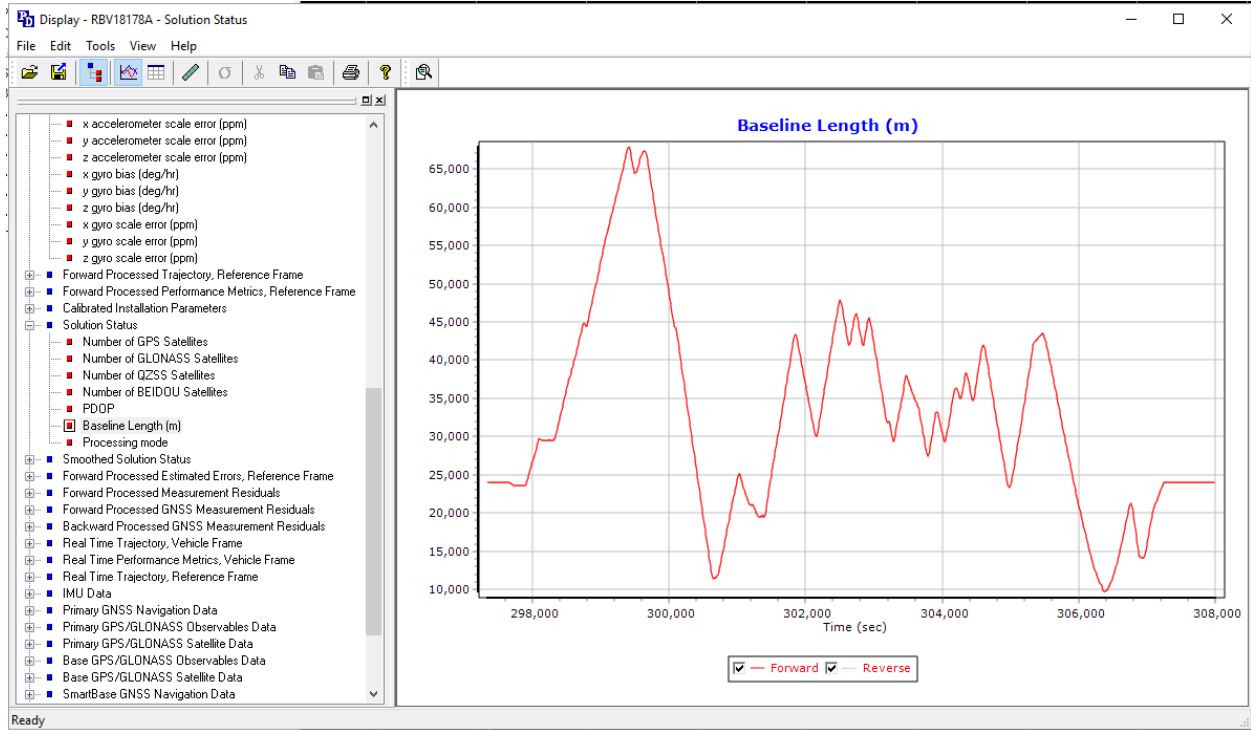
RBV18178A

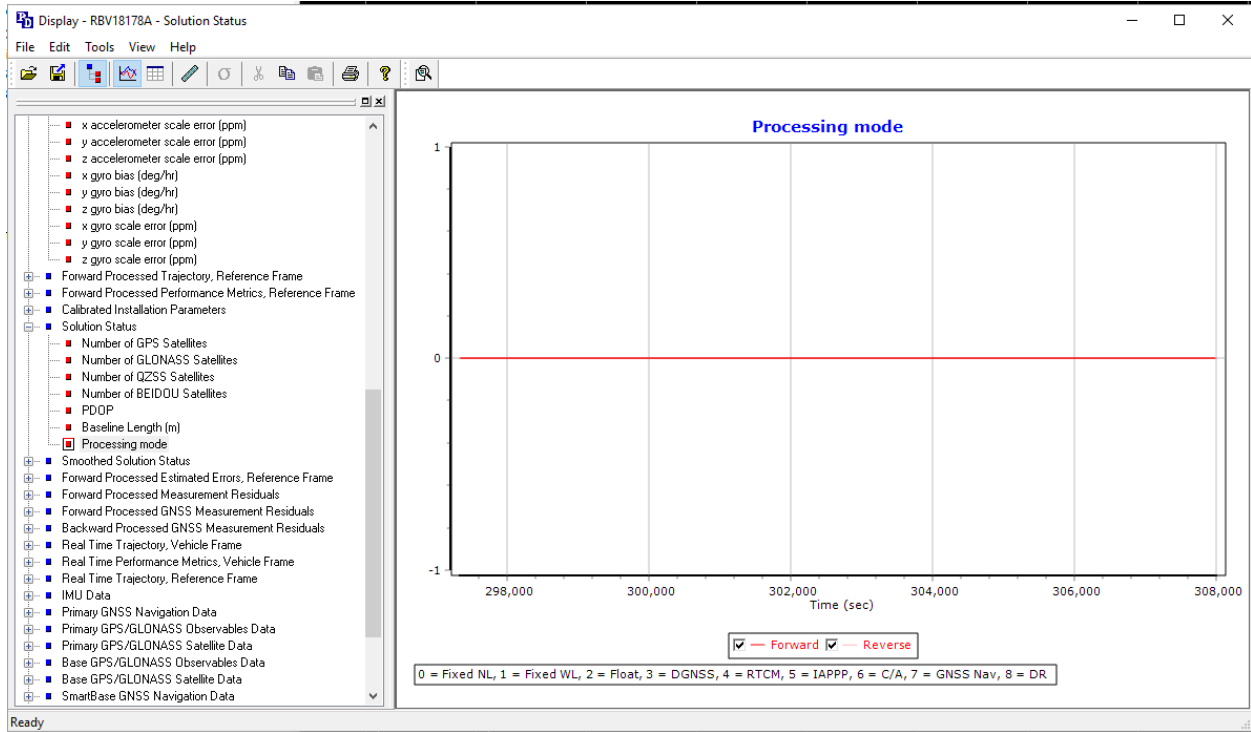




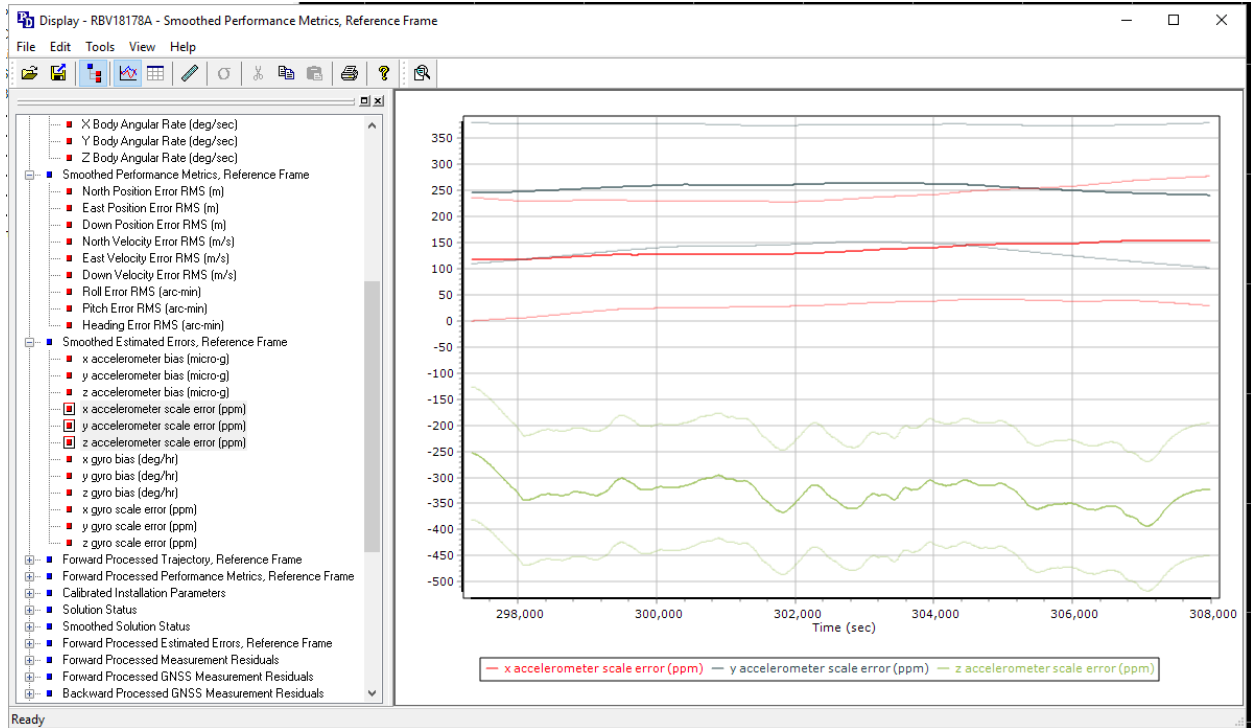
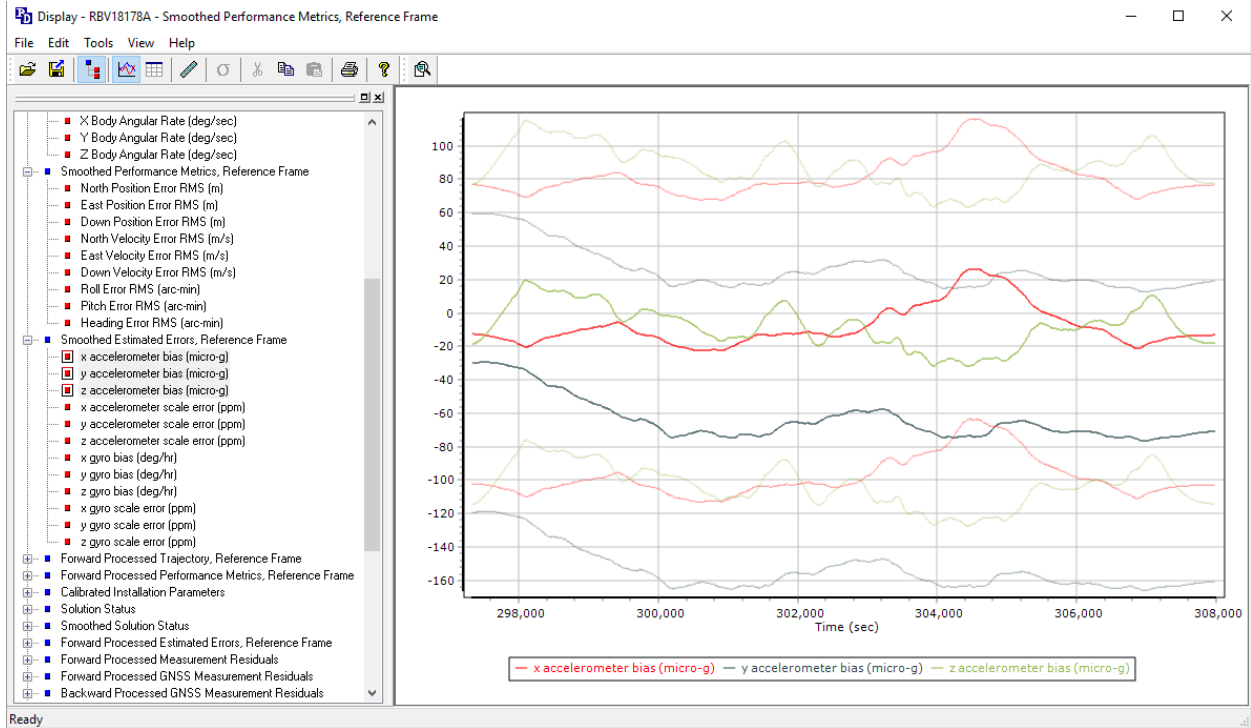


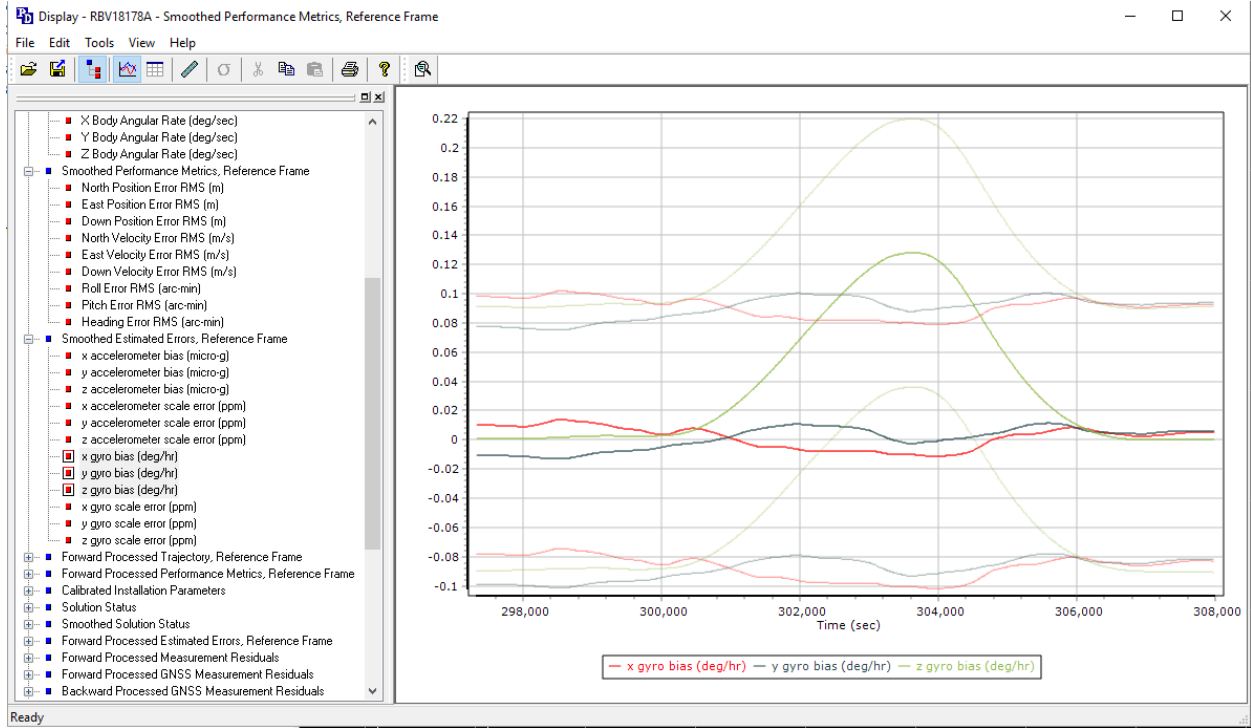




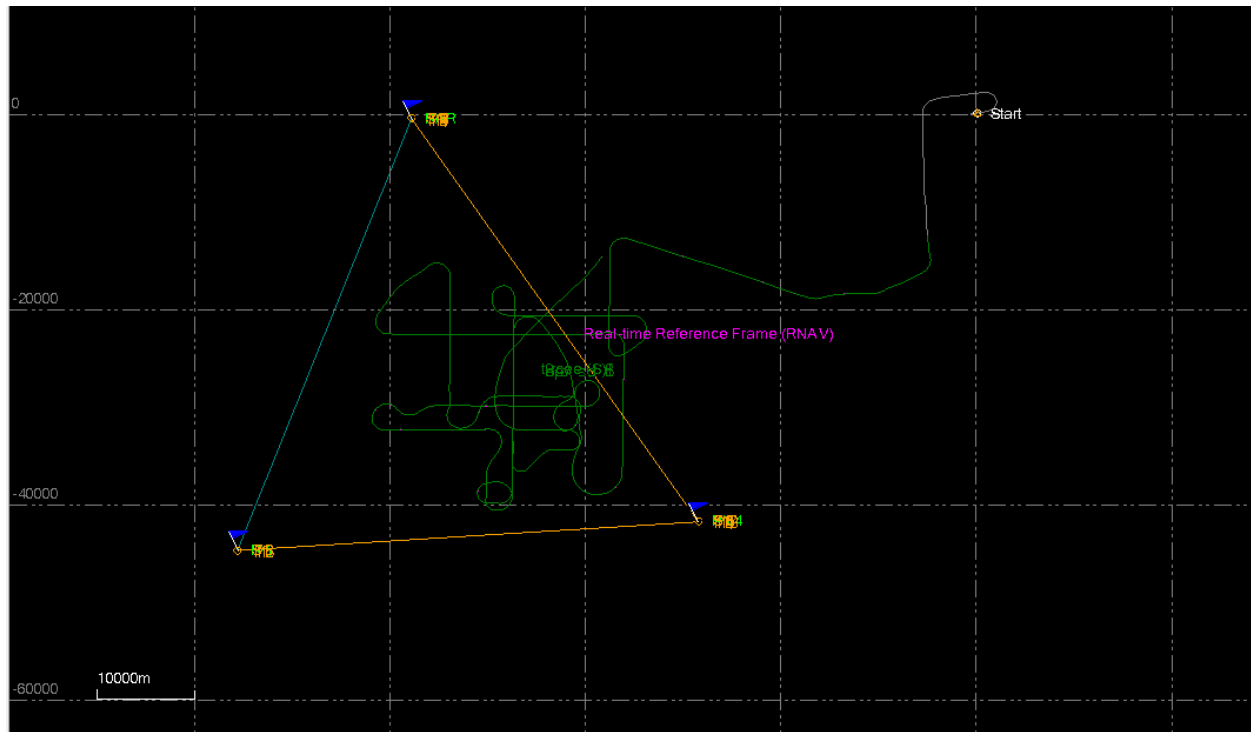


Sensor Errors





RBV18179A



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	-0.034 m
Y	-0.010 m
Z	-0.352 m

Stabilized Mount to IMU Mounting Angles

X	0.000 deg
Y	0.000 deg
Z	0.000 deg

Stabilized Mount to Primary GNSS Lever Arm

X	-0.037 m
Y	0.007 m
Z	-0.985 m

Aircraft to Stabilized Mount Mounting Angles

X	0.000 deg
Y	0.000 deg
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

Timing

Start: 385902.466

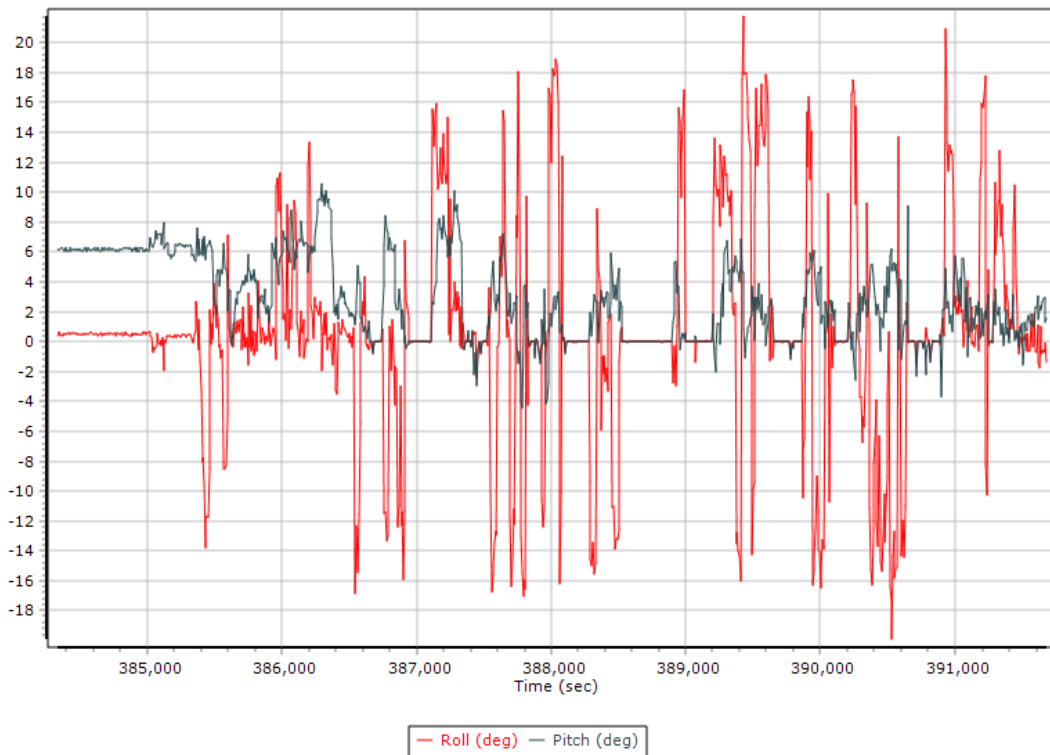
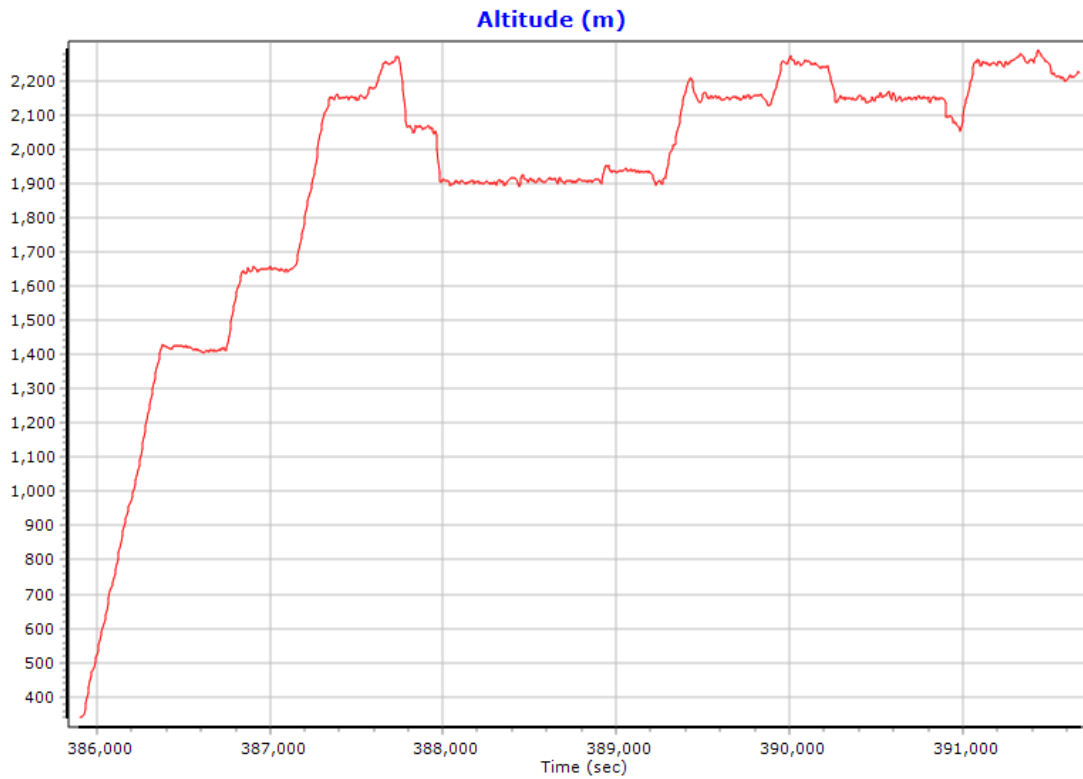
End: 391684.000

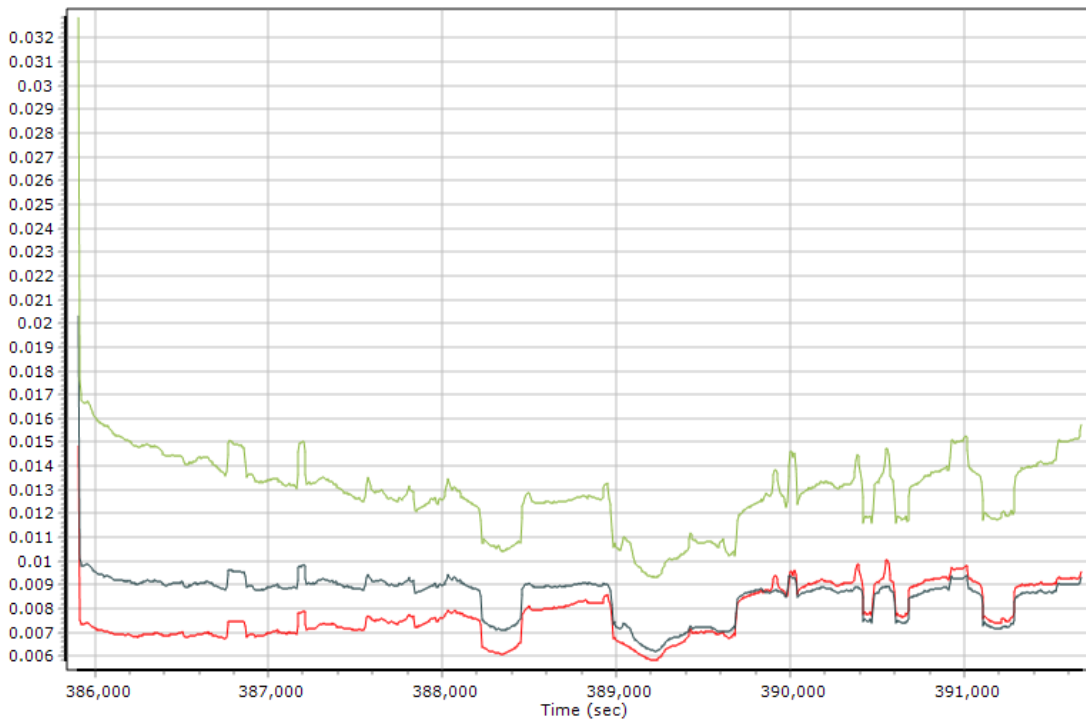
Entire time interval

Seconds of start week

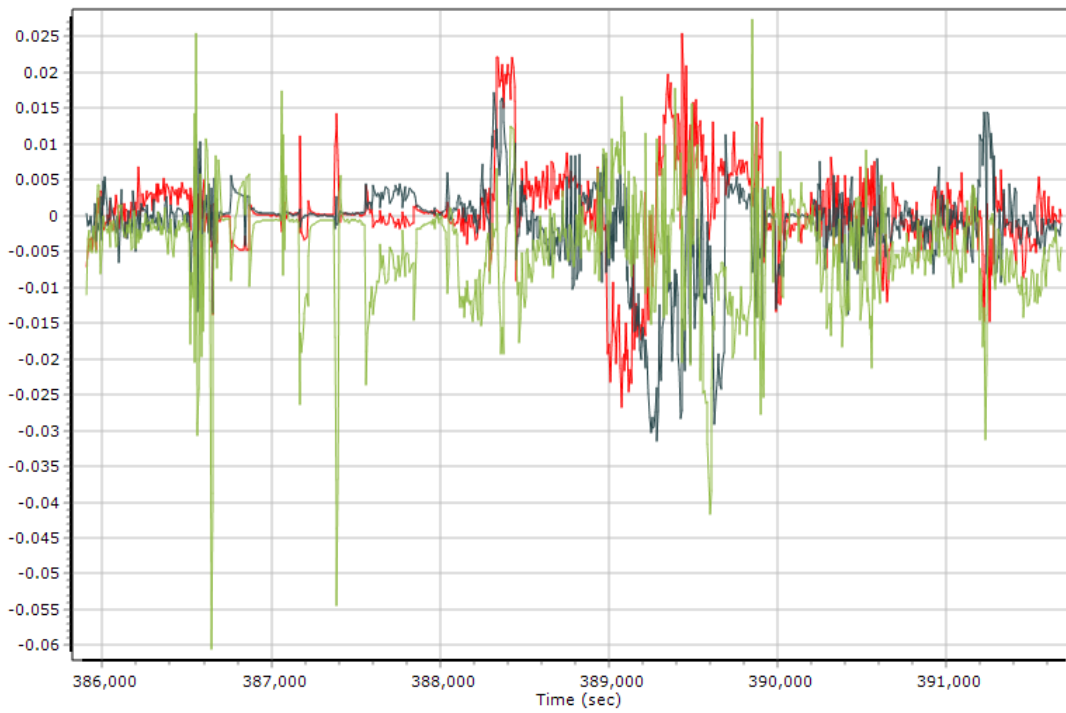
UTC Offset: 18.000

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

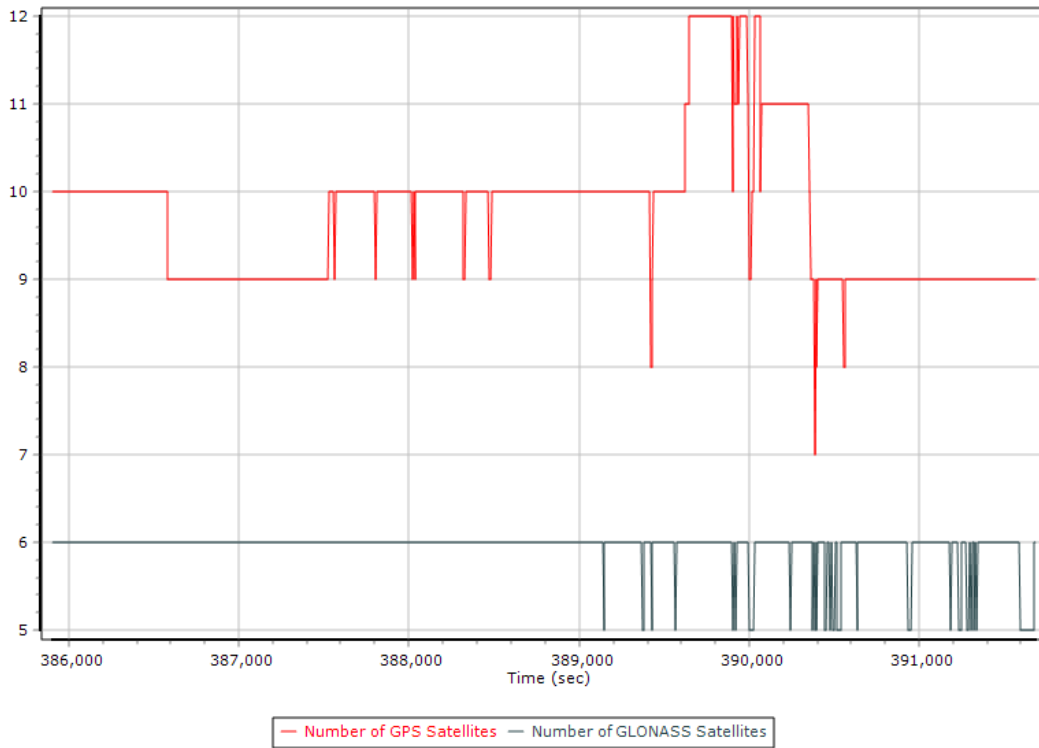




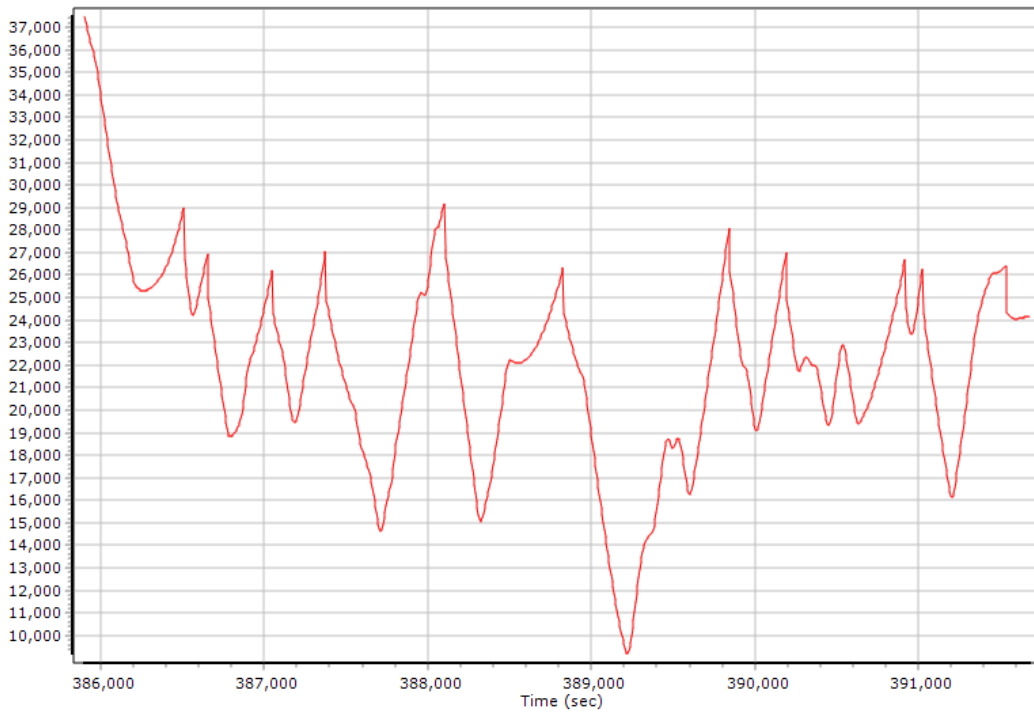
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



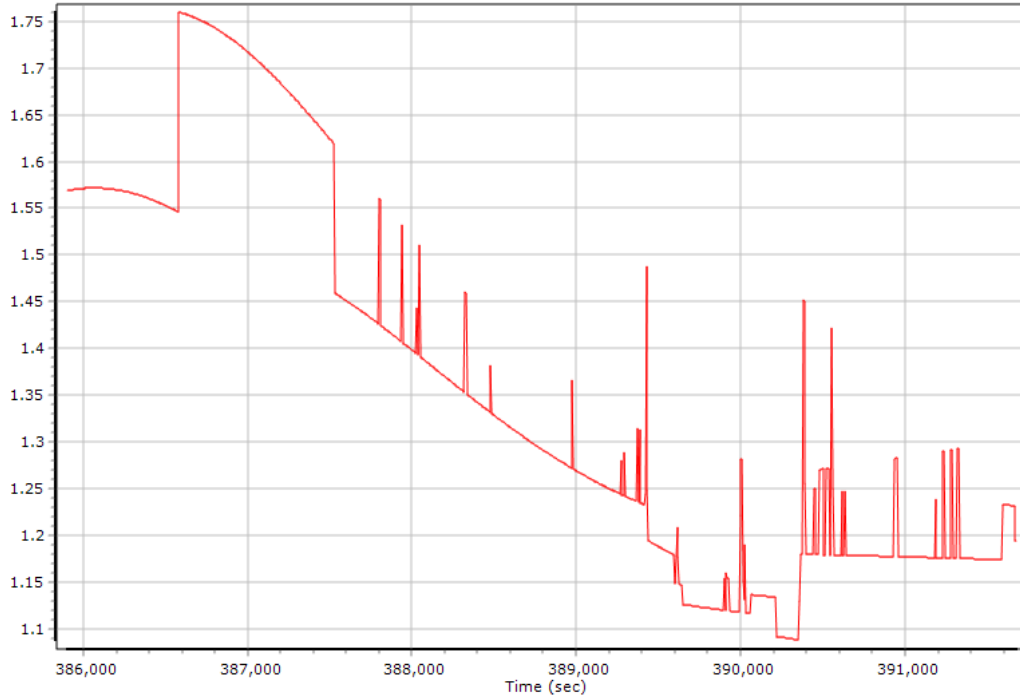
— North (m) — East (m) — Down (m) — DR mode



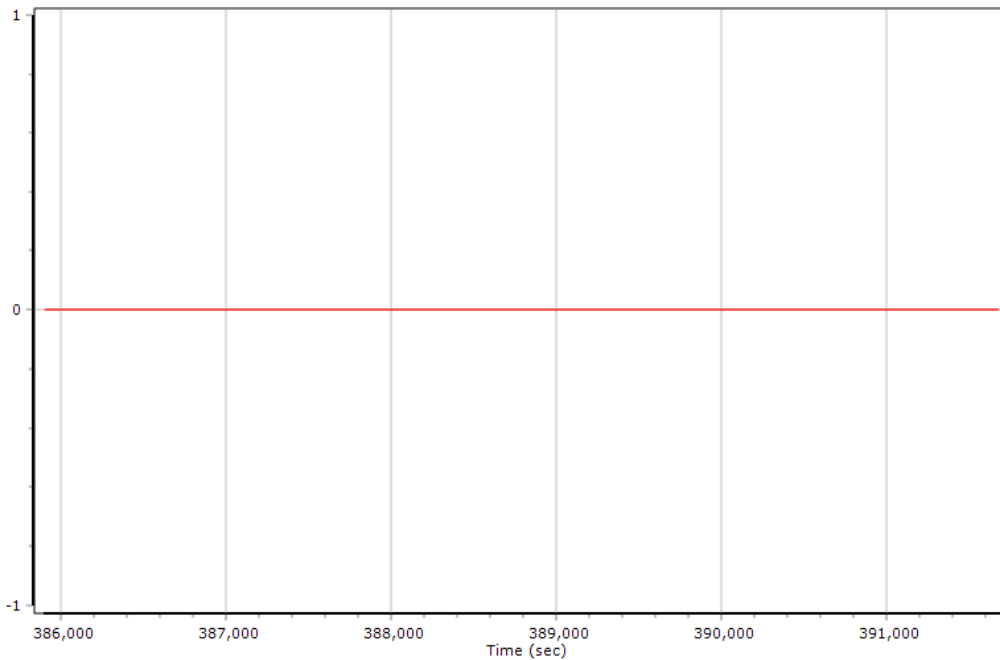
Baseline Length (m)



PDOP

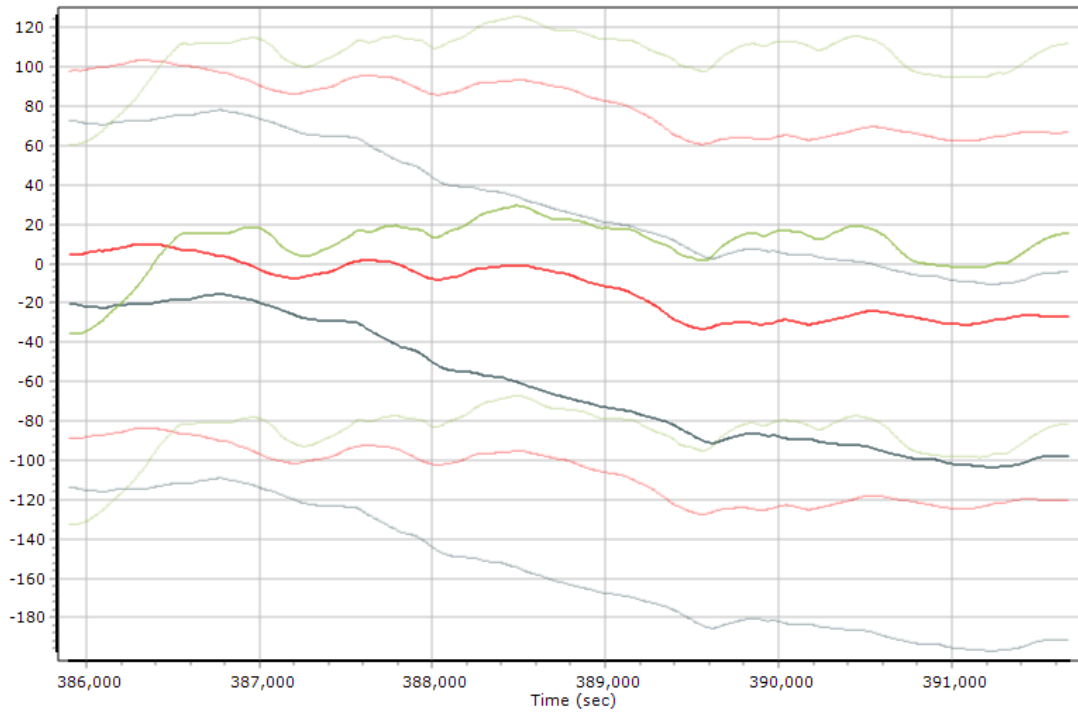


Processing mode

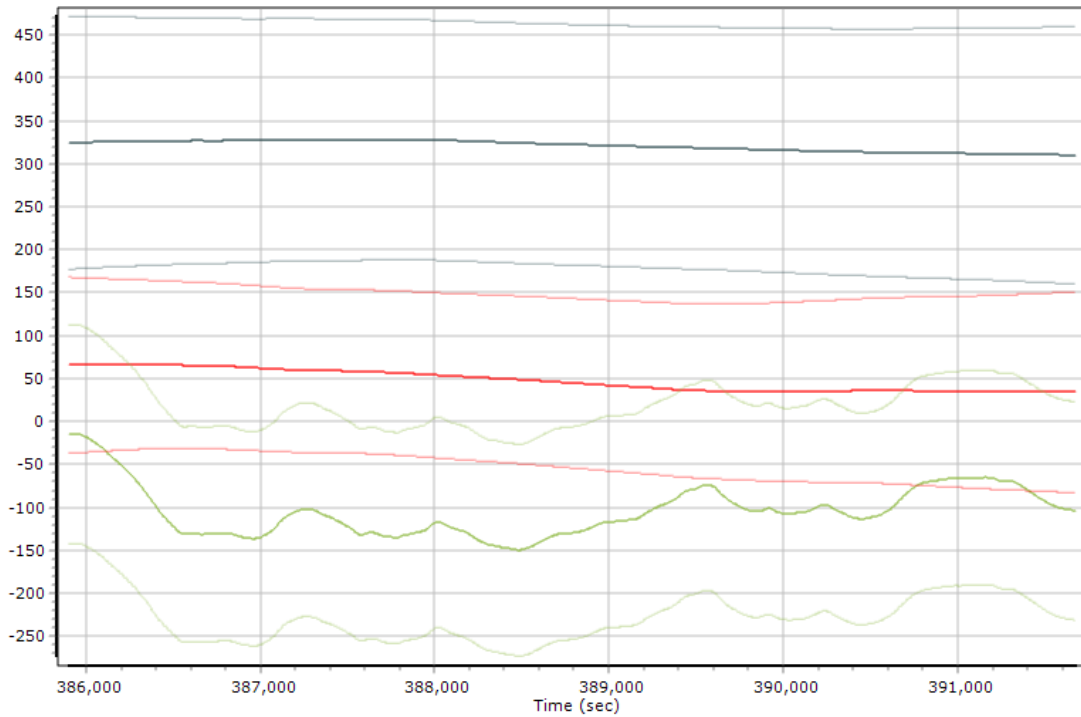


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

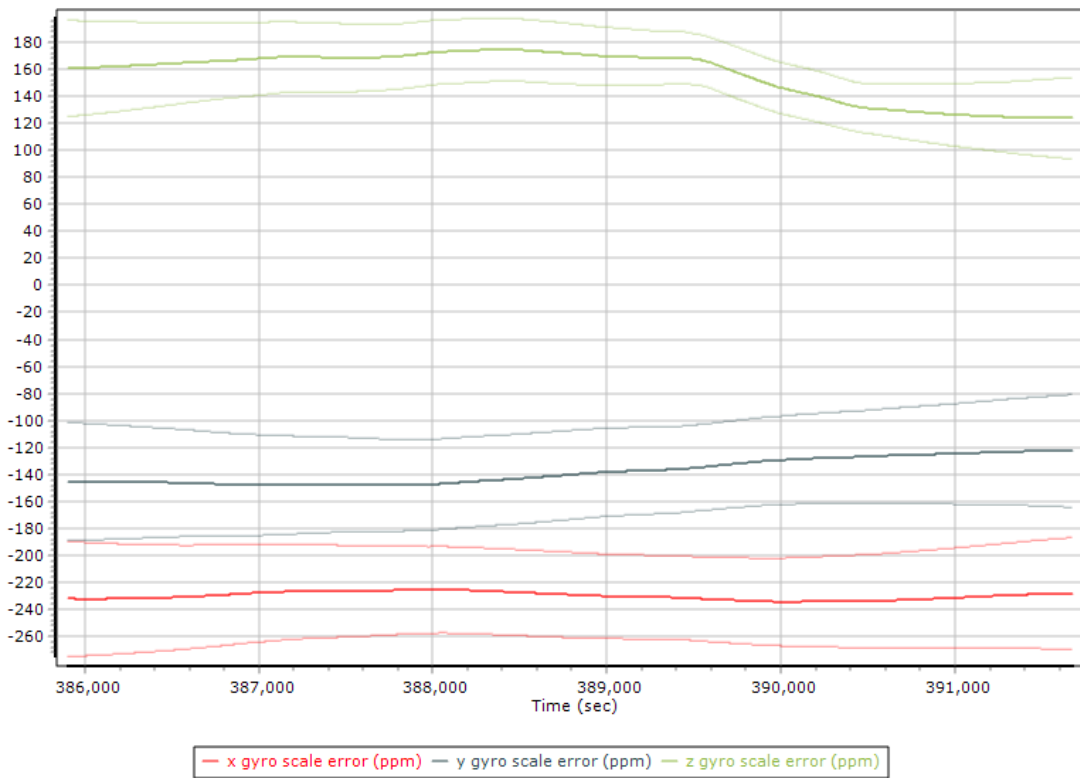
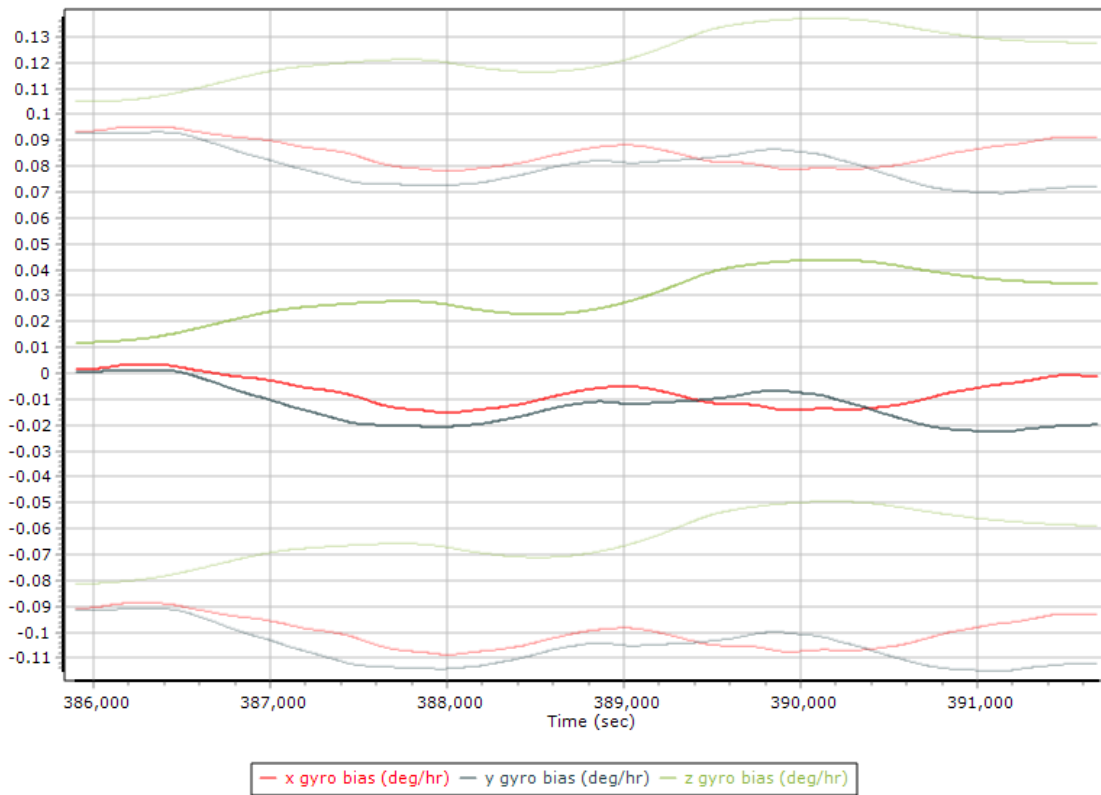
Sensor Errors



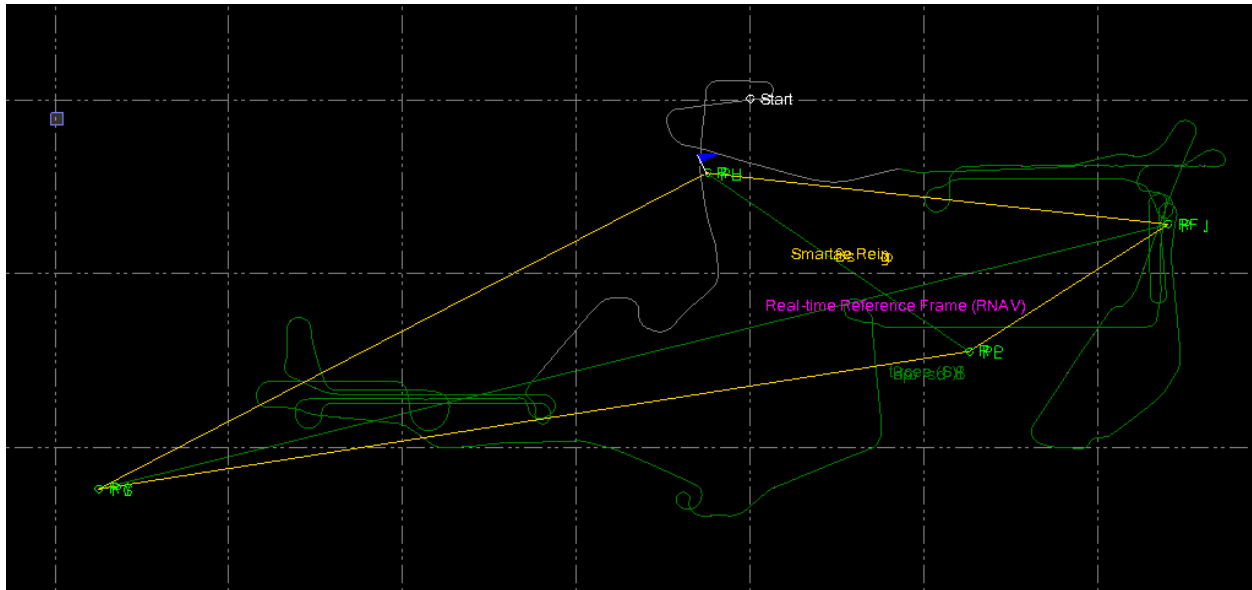
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



RBV18182A



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

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: -0.037 m	X: 0.000 deg
Y: 0.007 m	Y: 0.000 deg
Z: -0.985 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

Project Settings interface showing a sidebar menu and a main configuration panel.

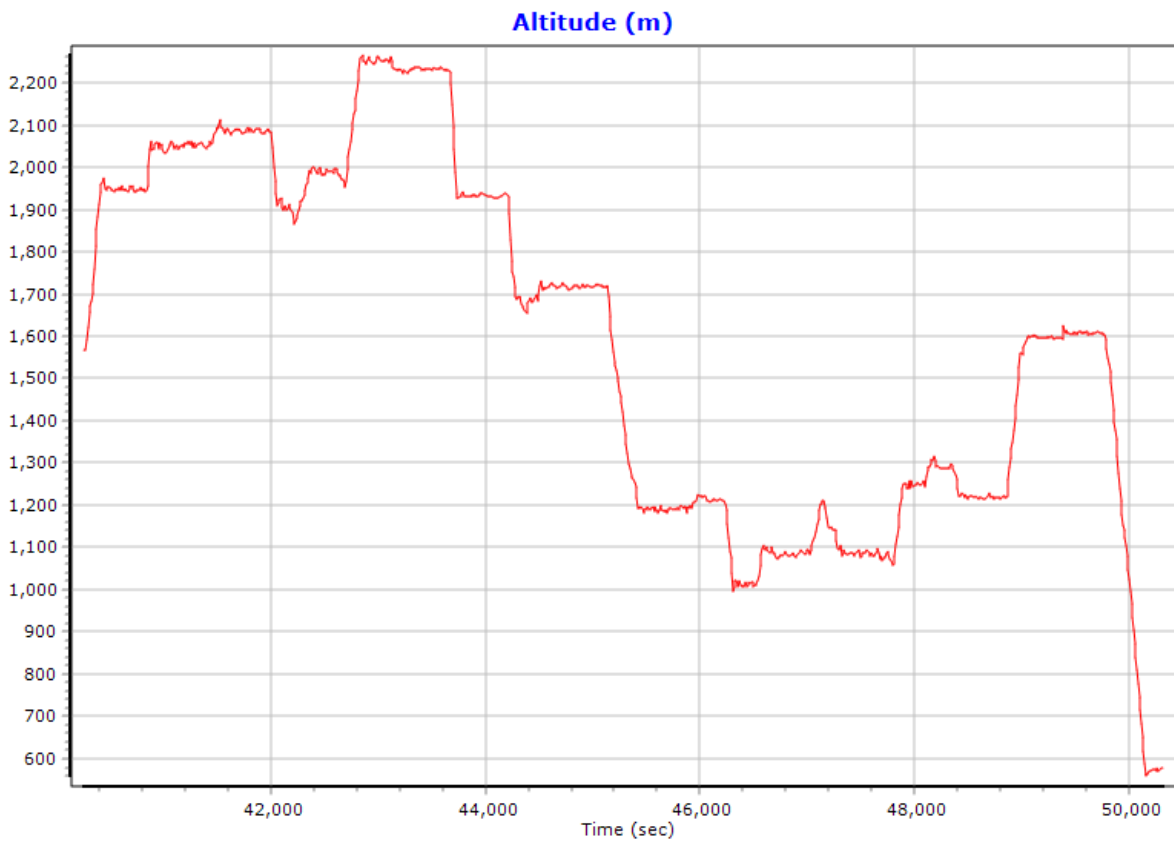
Timing

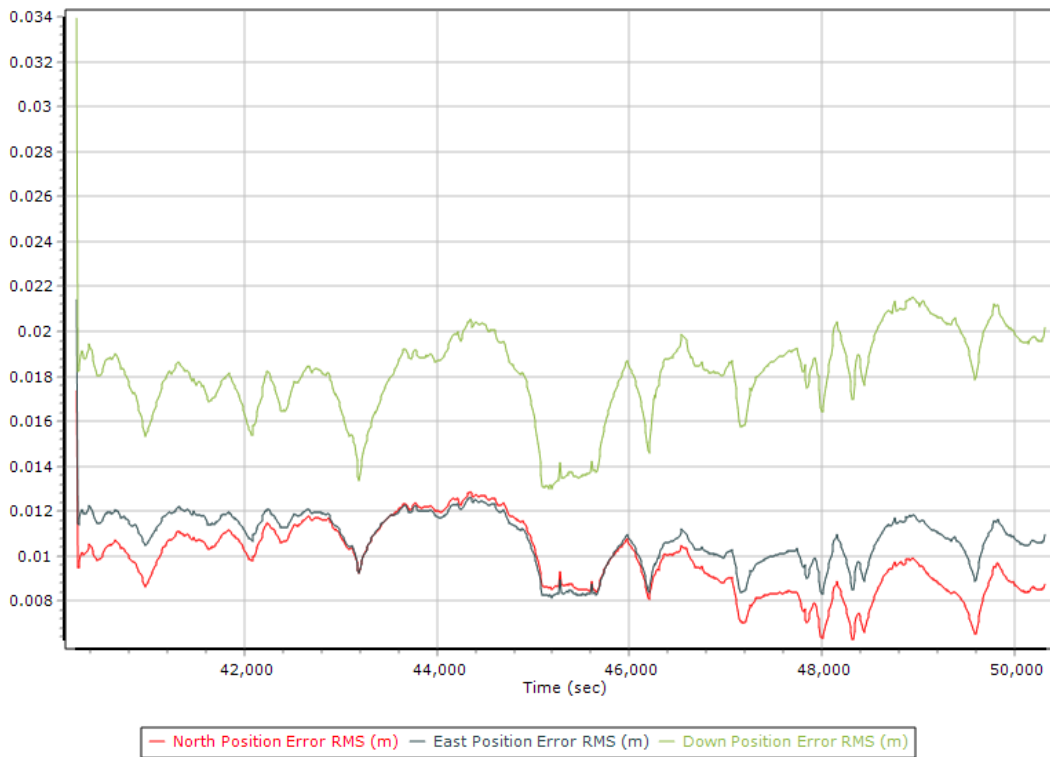
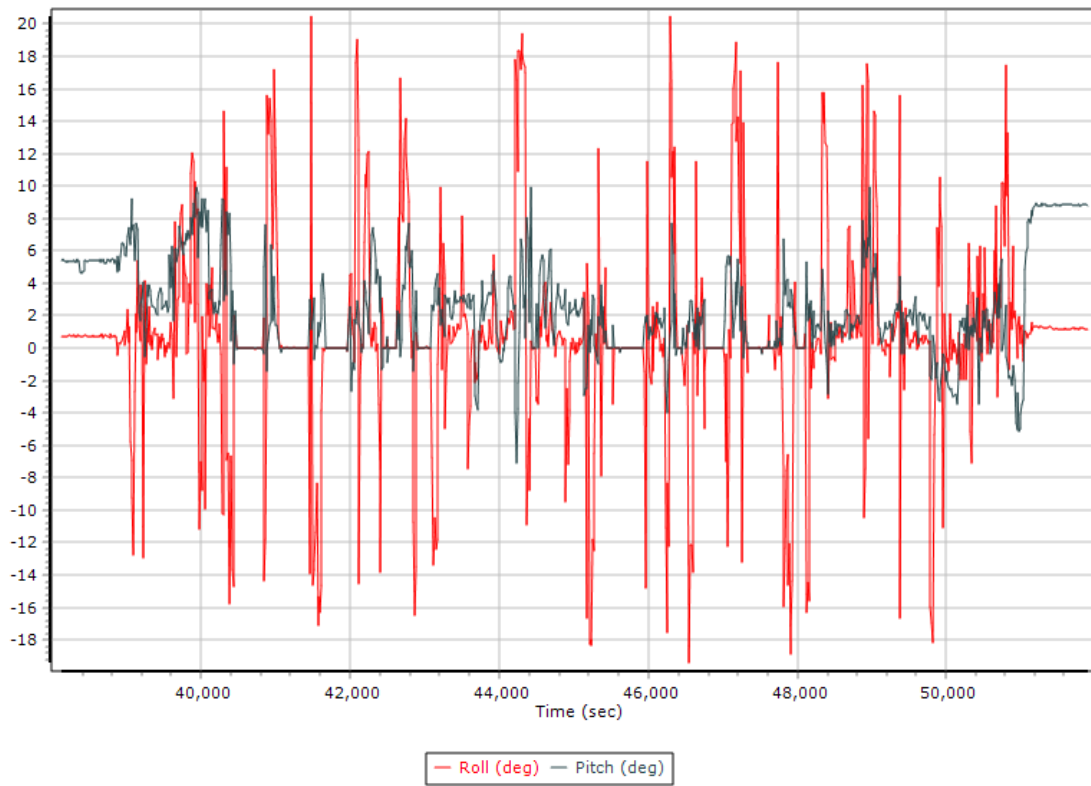
Start: 40251.088
End: 50333.465

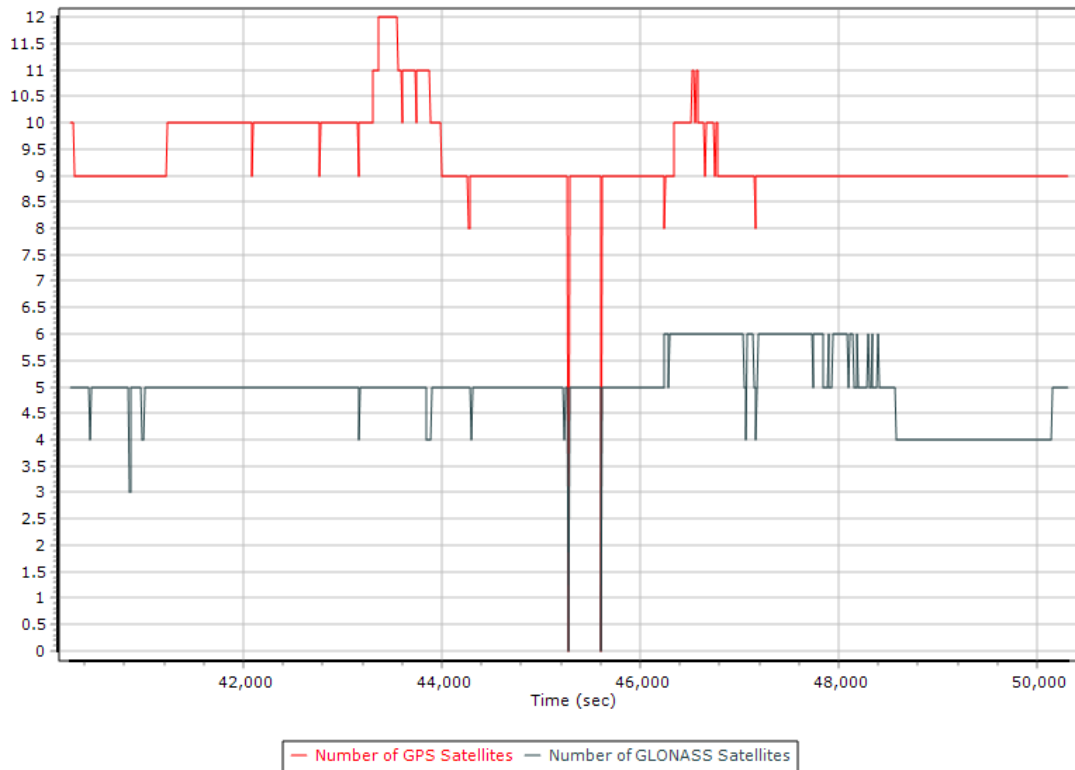
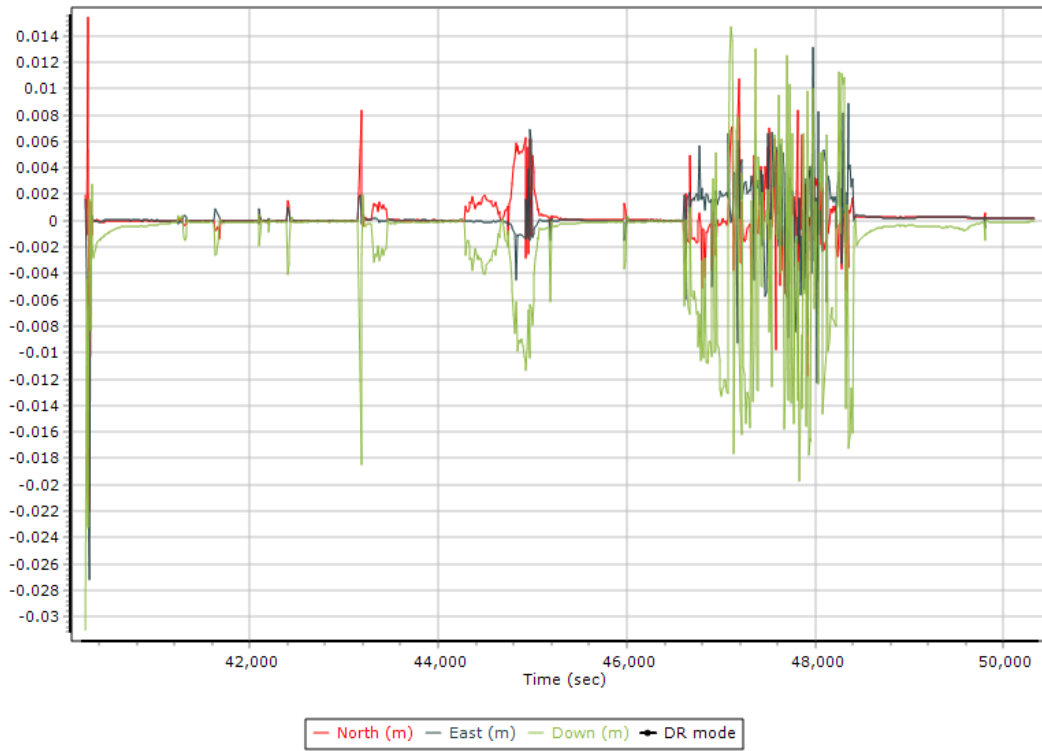
Entire time interval
 Seconds of start week

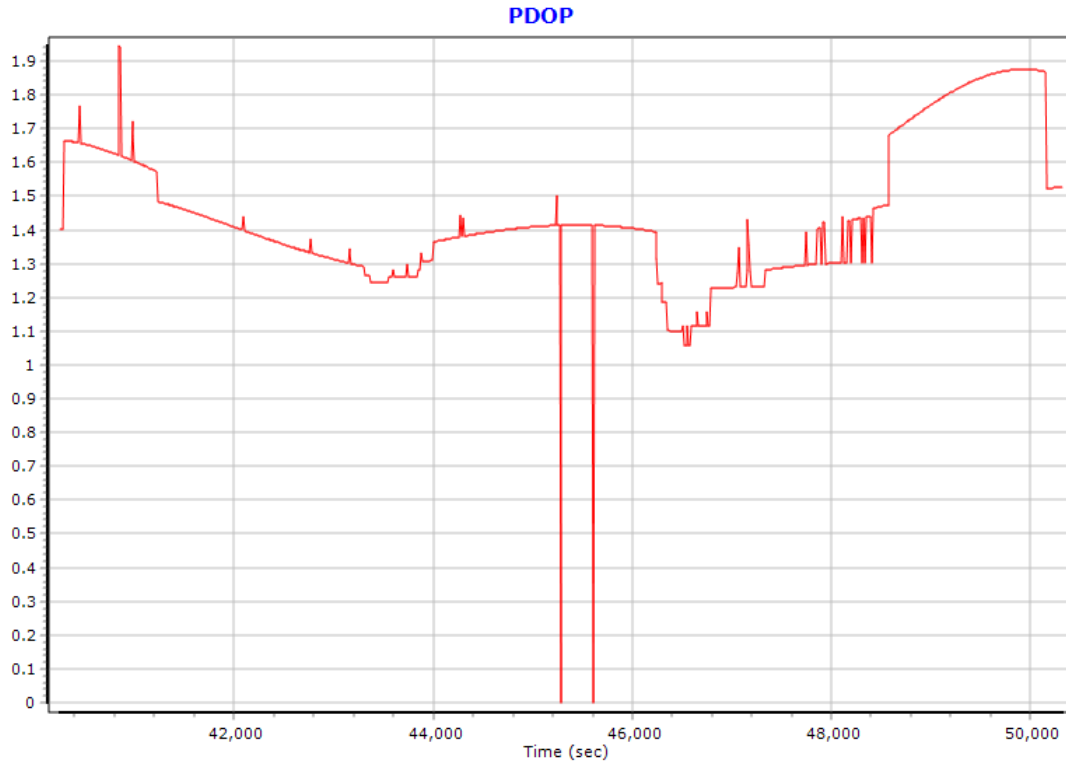
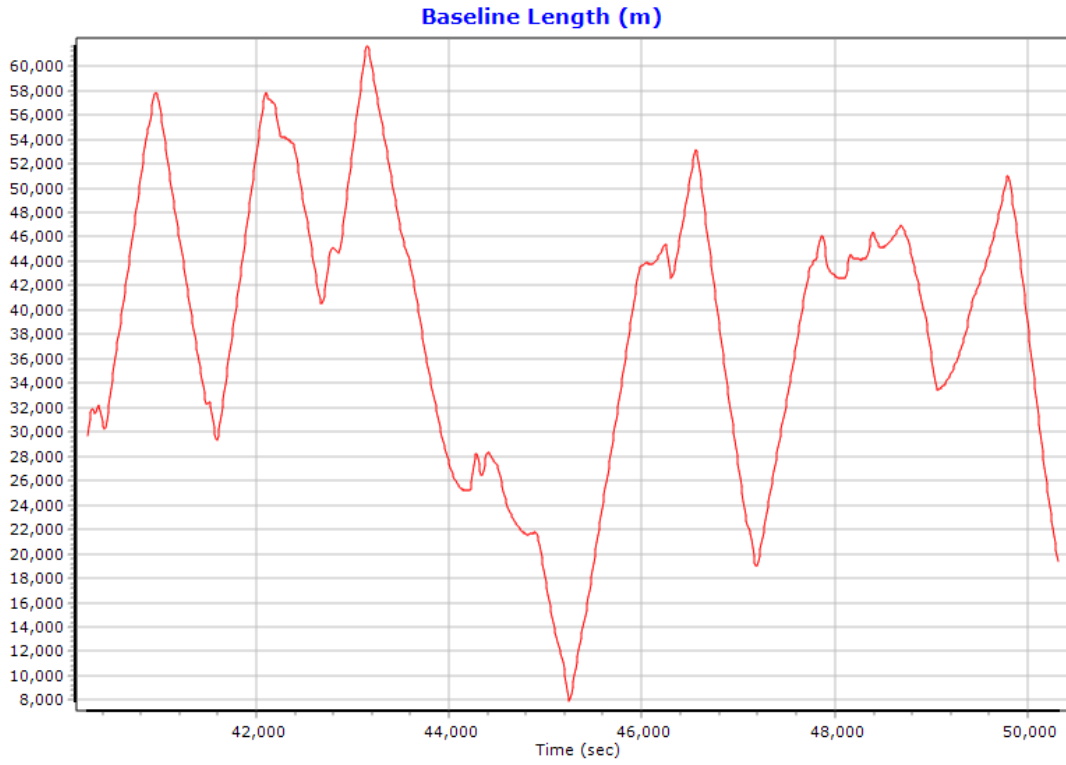
UTC Offset: 18.000

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

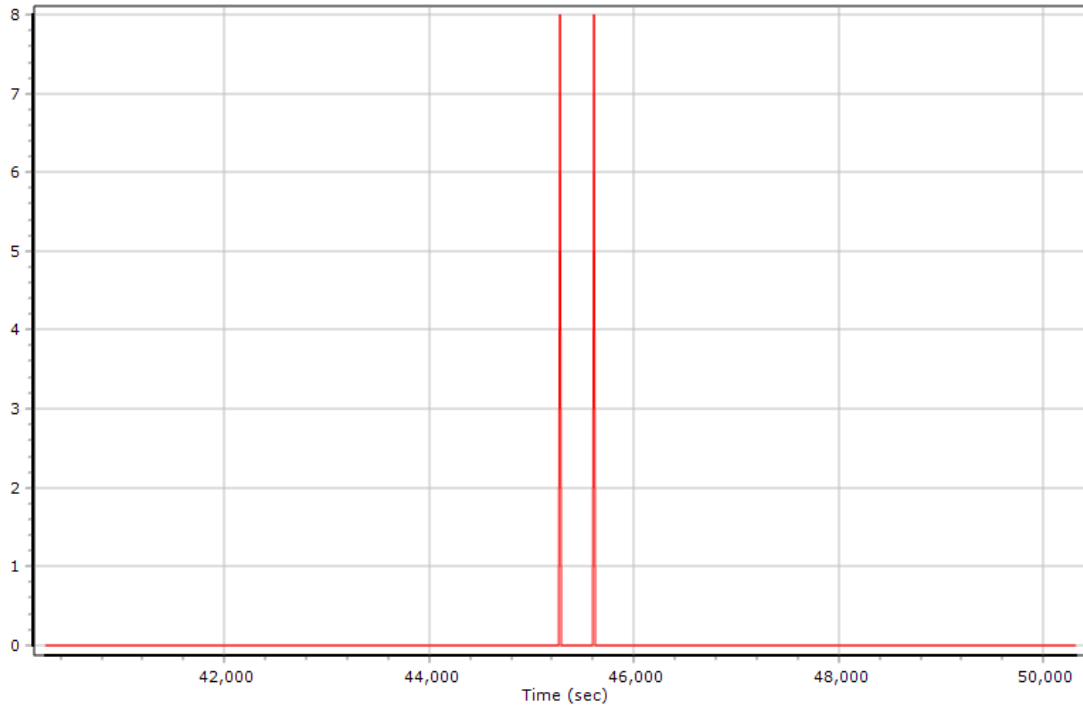






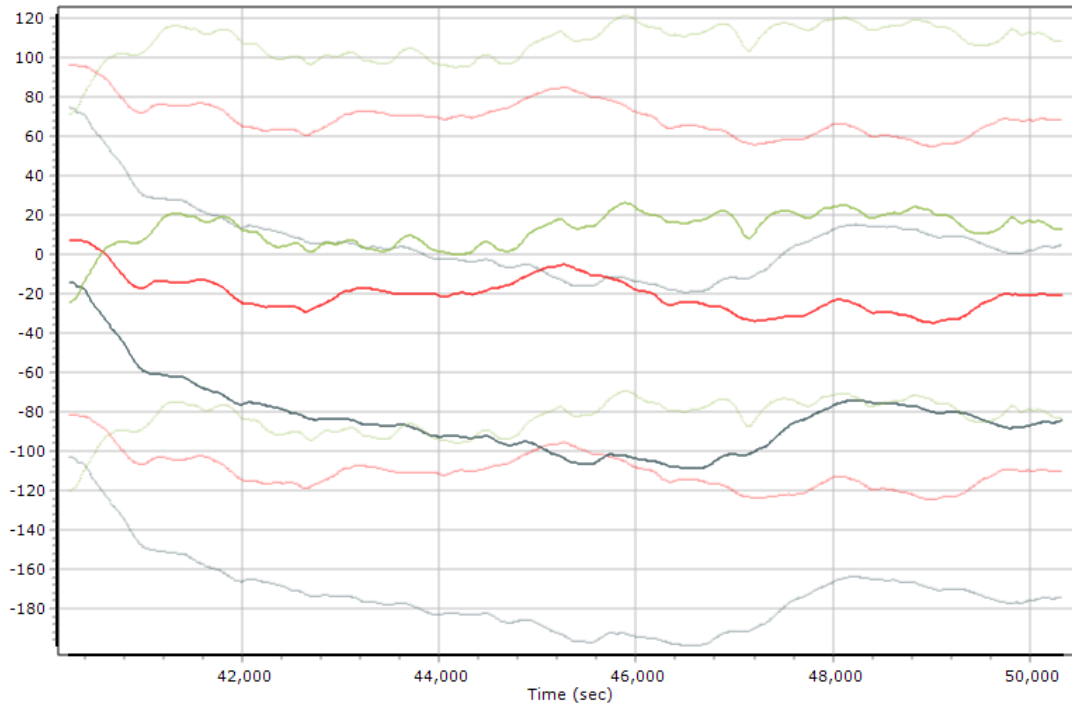


Processing mode

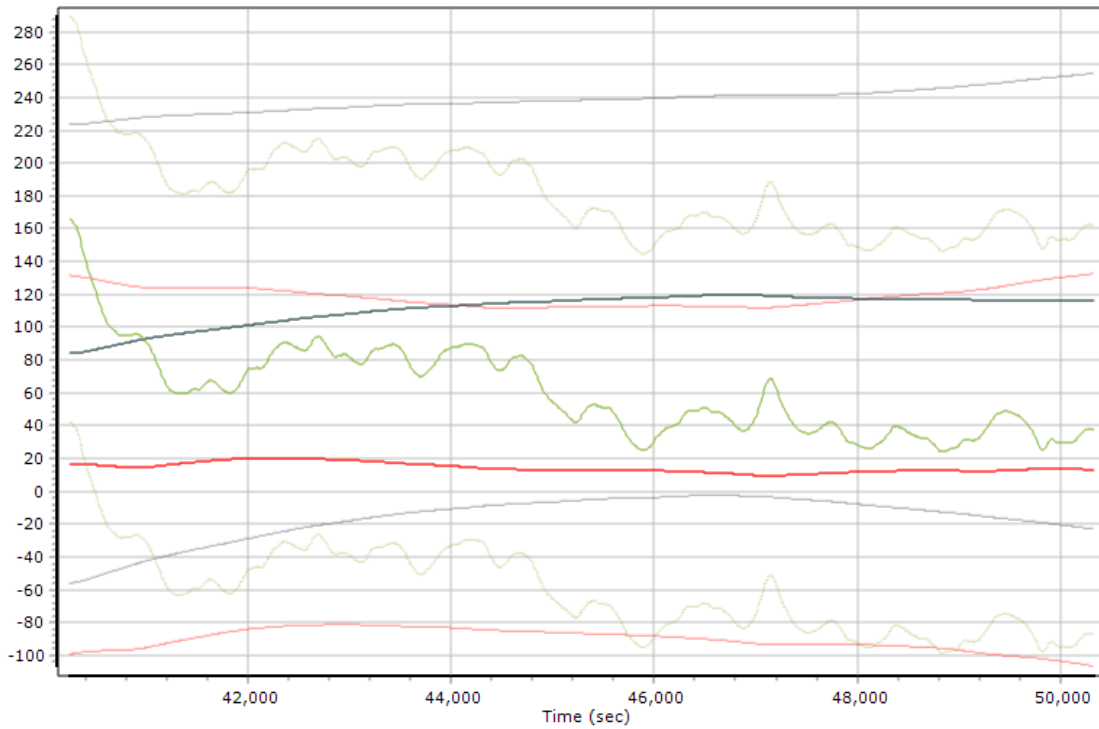


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

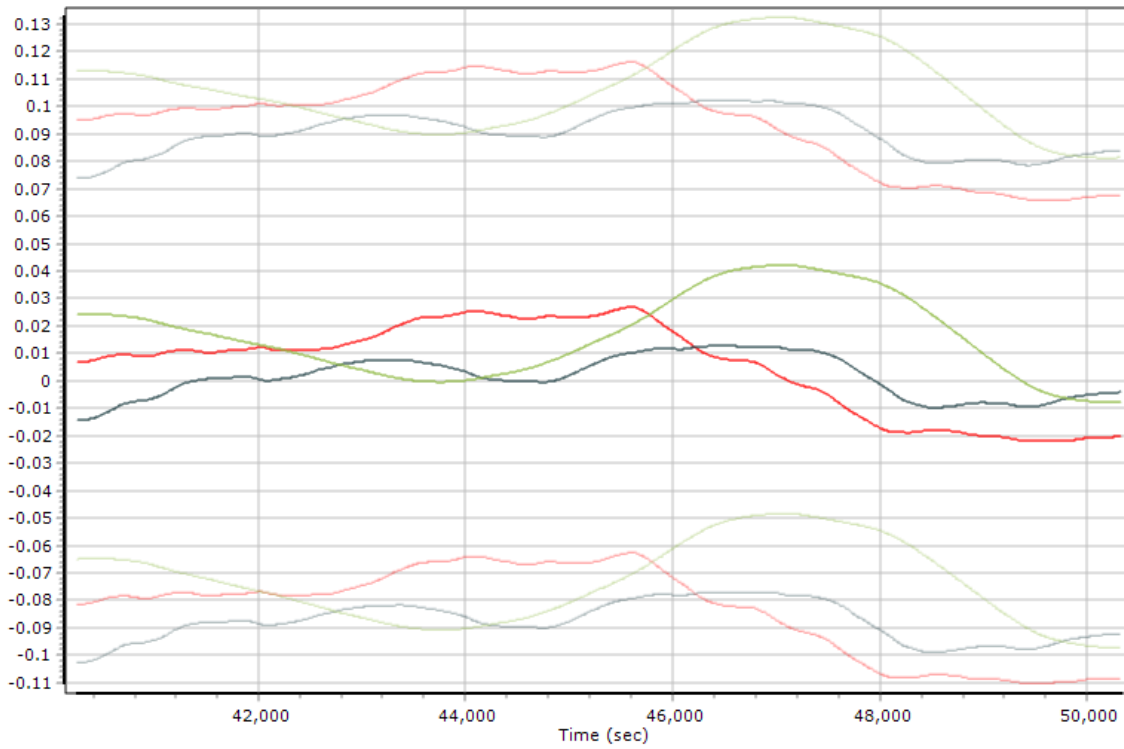
Sensor Errors



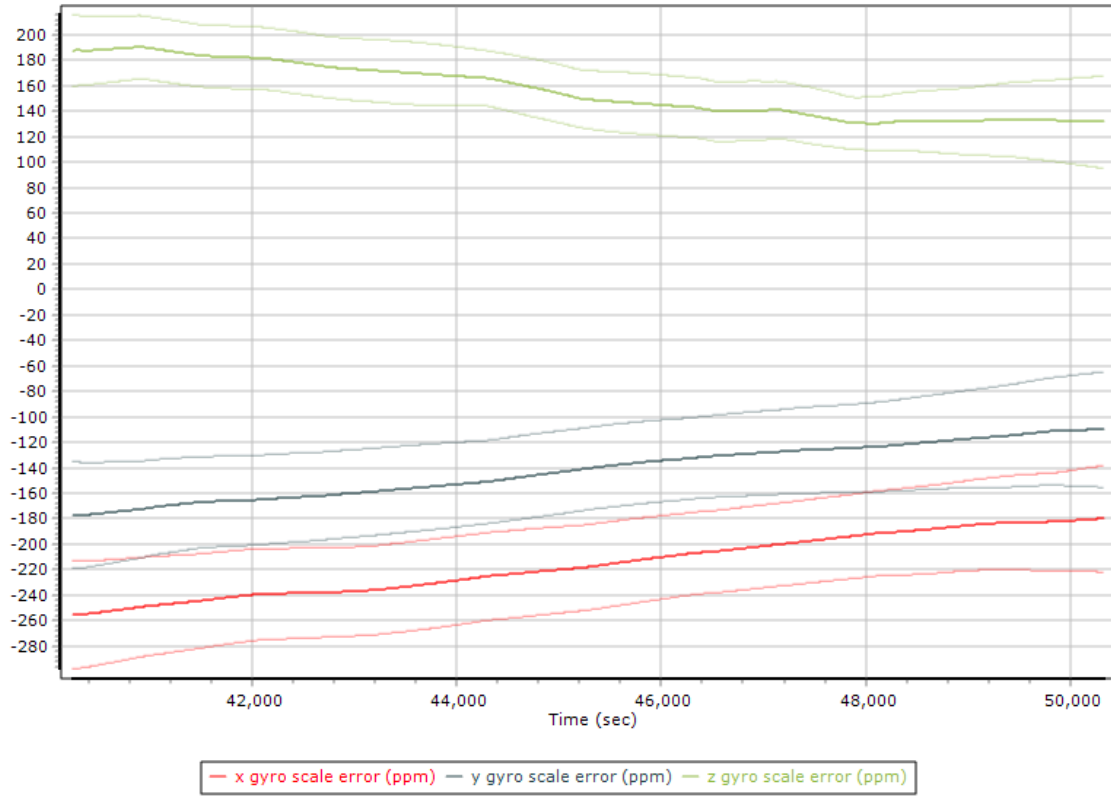
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



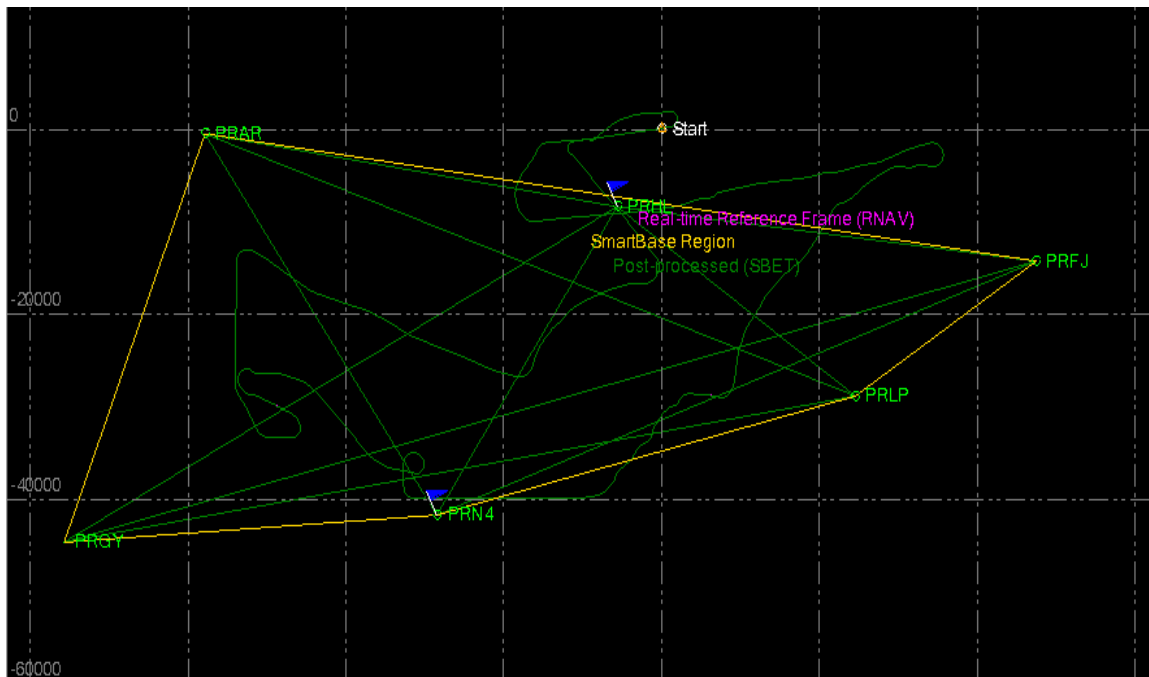
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)



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



RBV18183A



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: -0.034 m
Y: -0.010 m
Z: -0.352 m

Stabilized Mount to IMU Mounting Angles
X: 0.000 deg
Y: 0.000 deg
Z: 0.000 deg

Stabilized Mount to Primary GNSS Lever Arm
X: -0.037 m
Y: 0.007 m
Z: -0.985 m

Aircraft to Stabilized Mount Mounting Angles
X: 0.000 deg
Y: 0.000 deg
Z: 0.000 deg

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

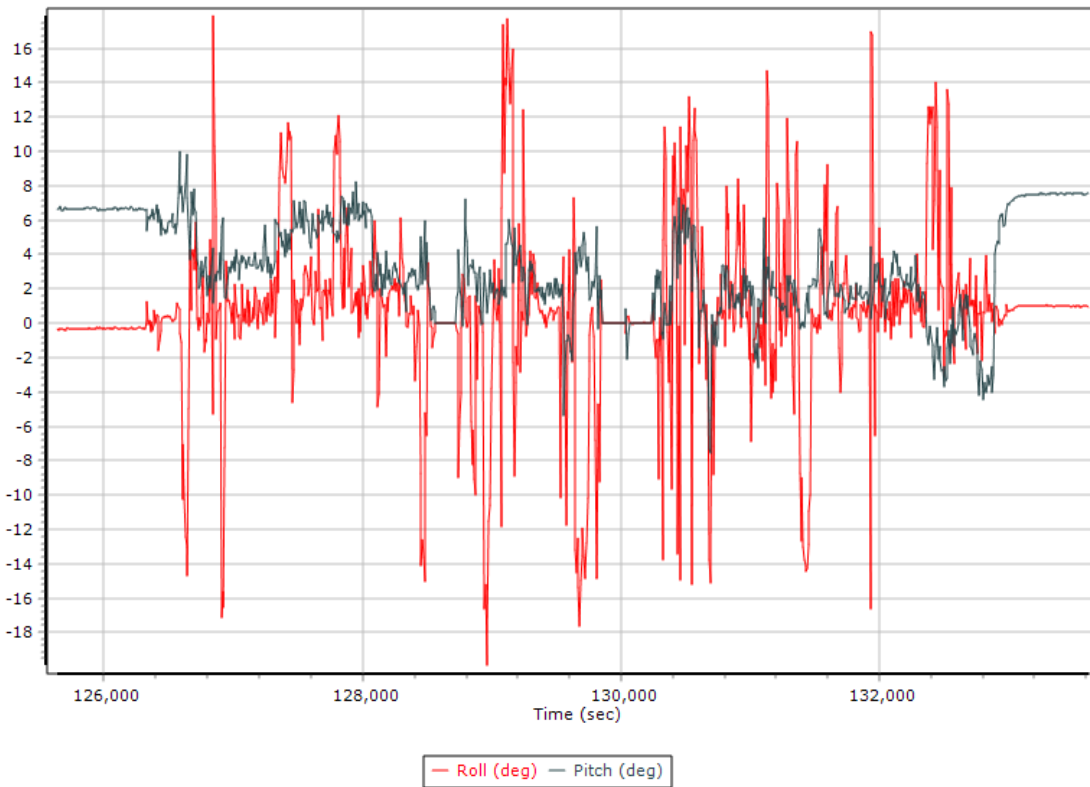
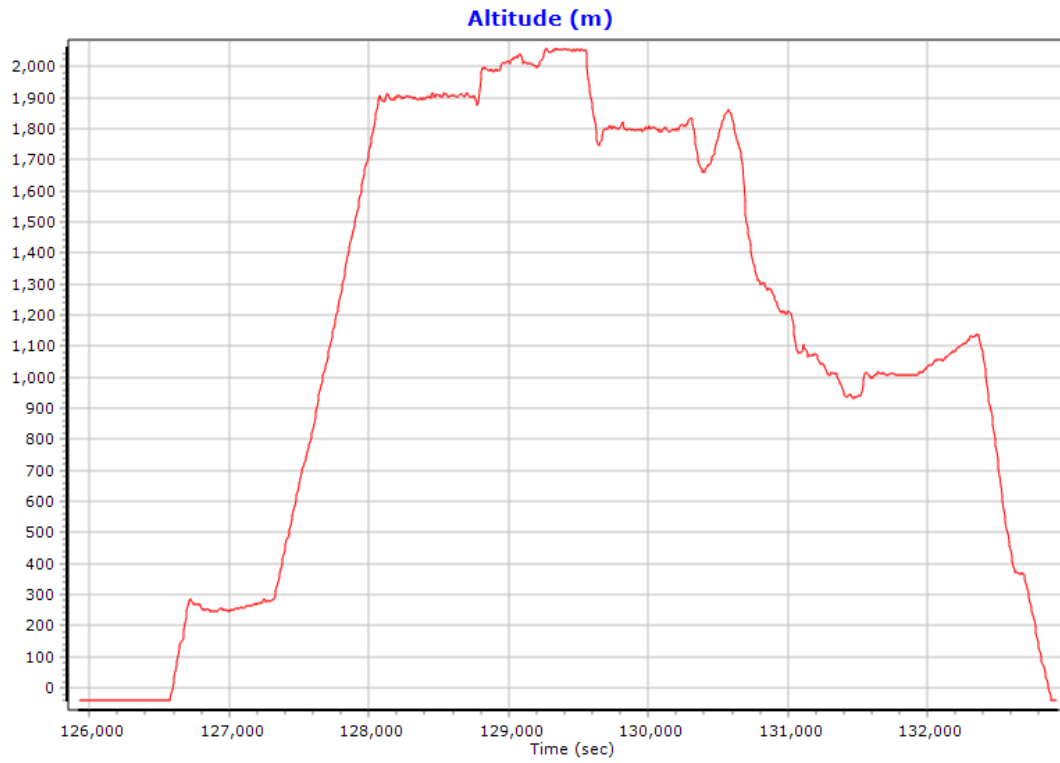
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

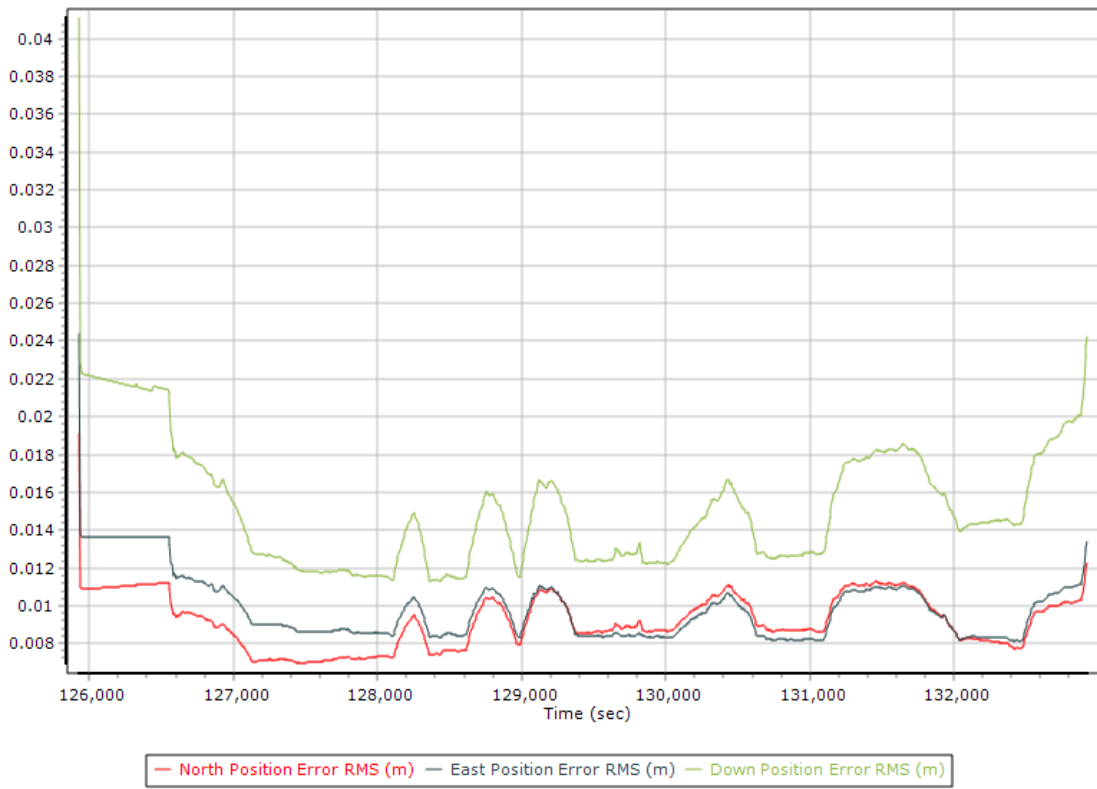
OK Cancel

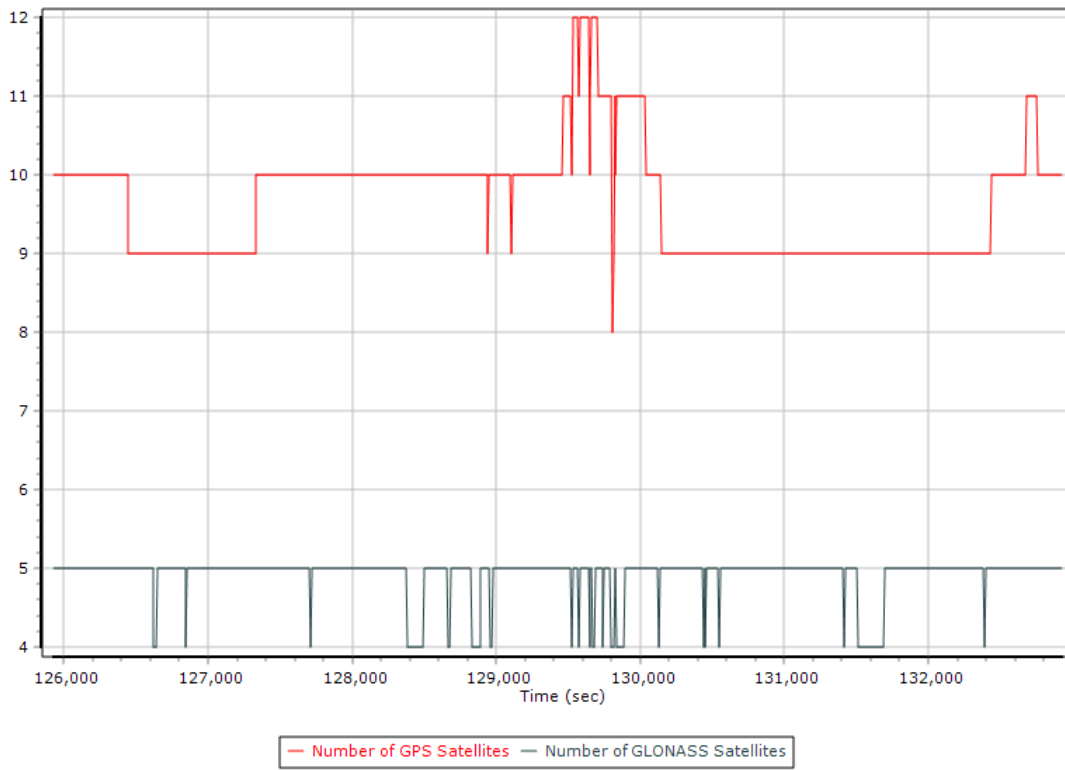
Timing

Start: 125639.000
End: 133620.000
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

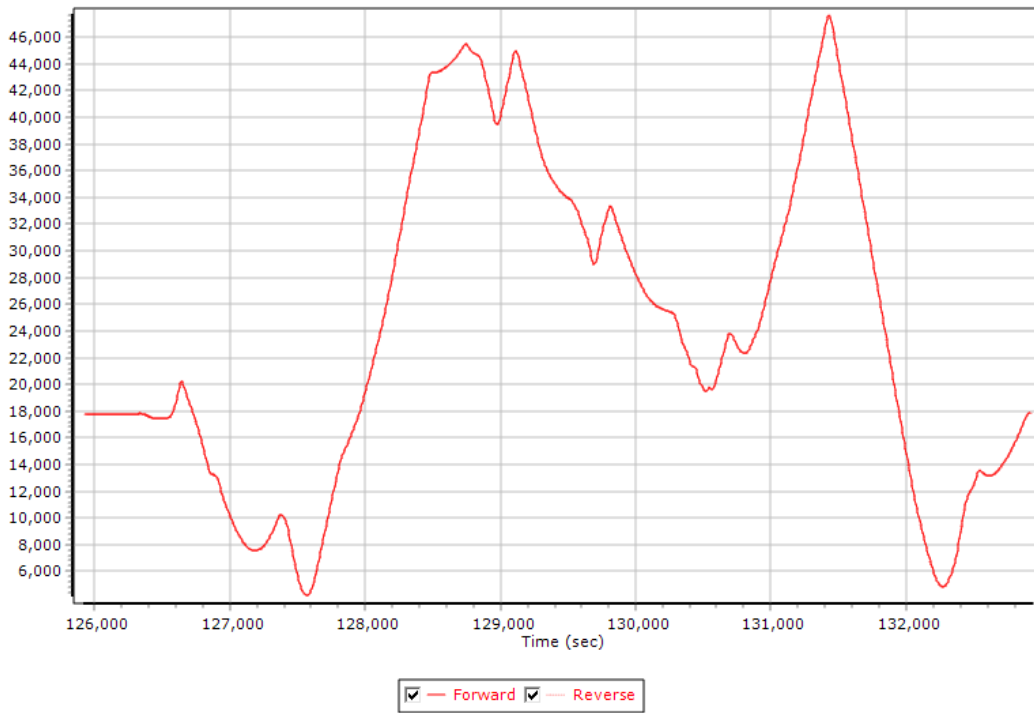
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



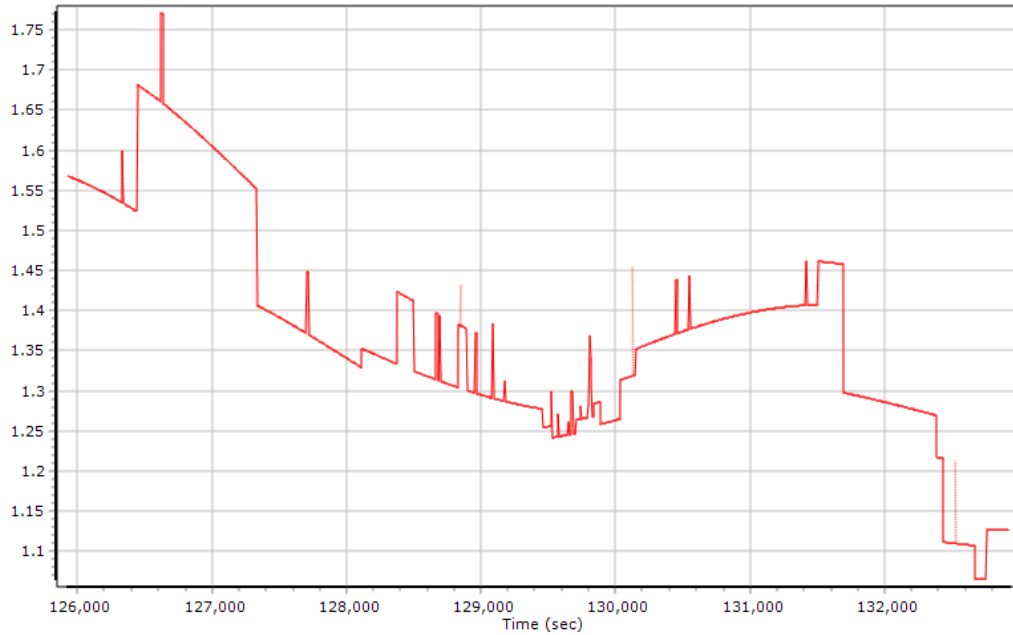




Baseline Length (m)

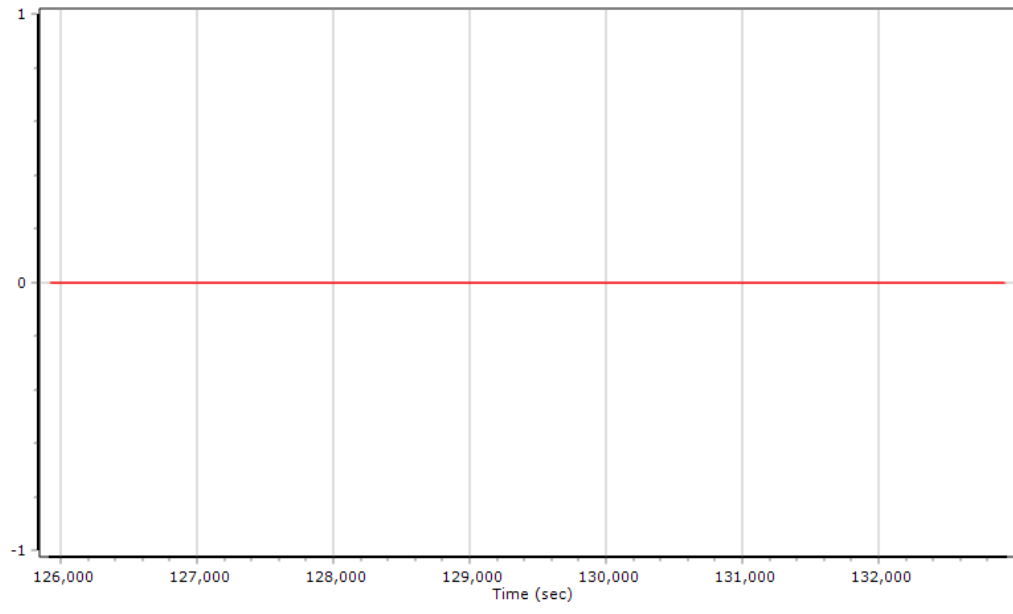


PDOP



Forward Reverse

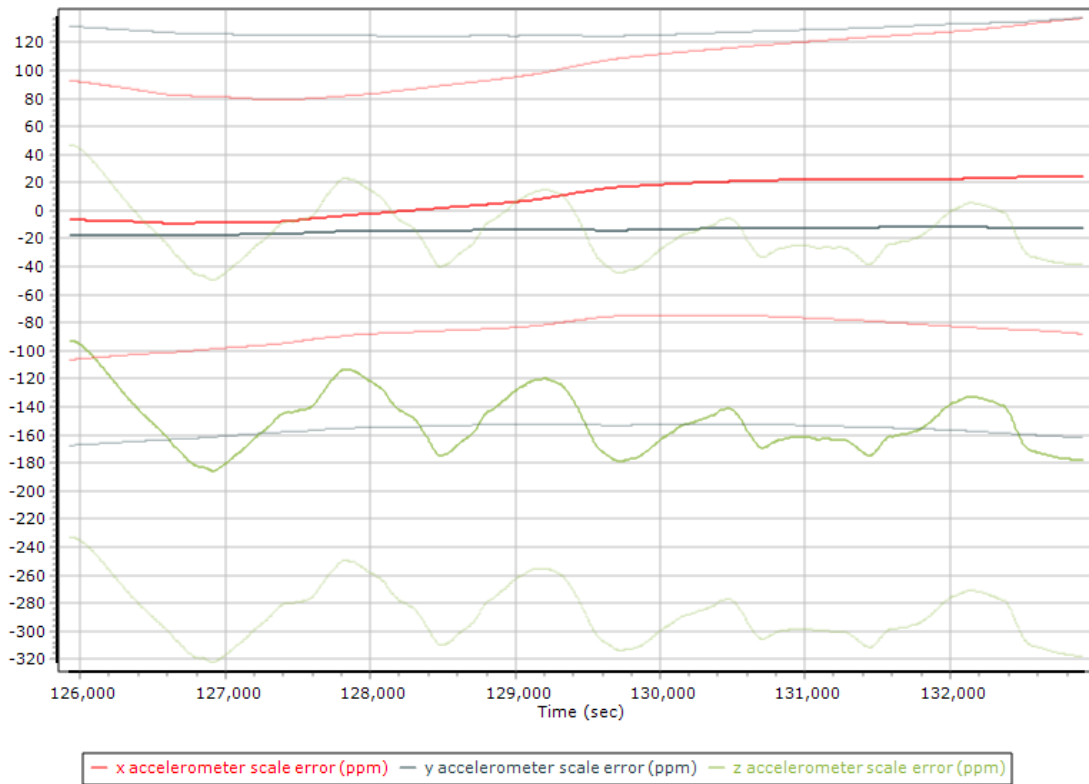
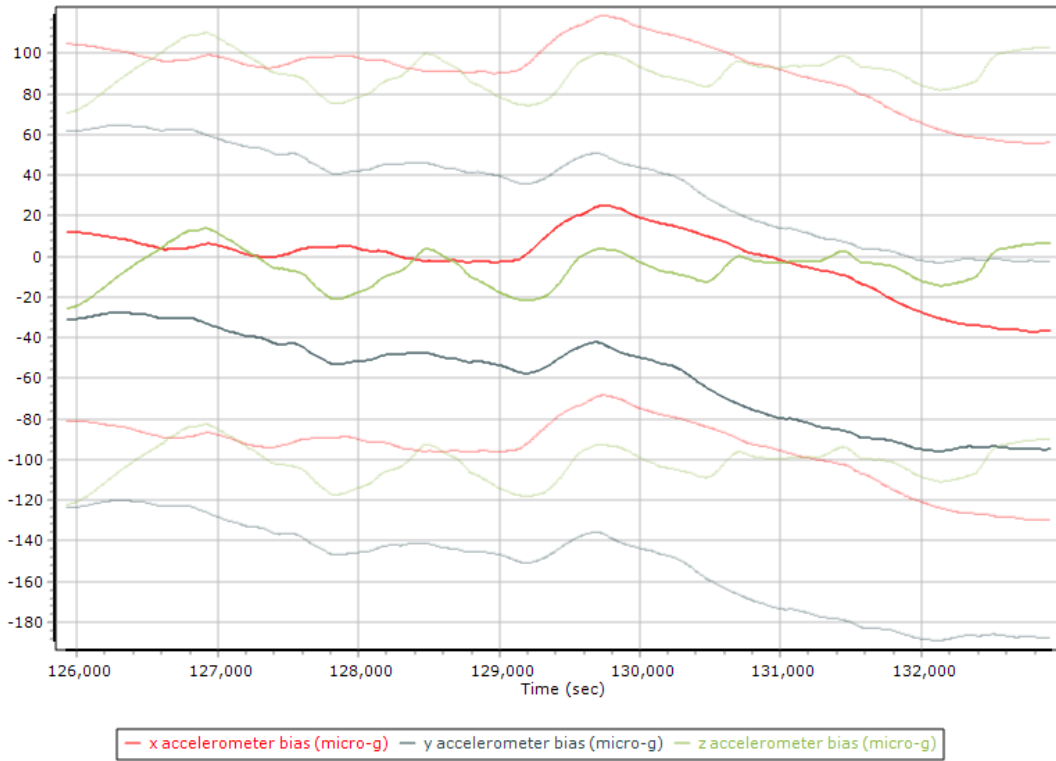
Processing mode

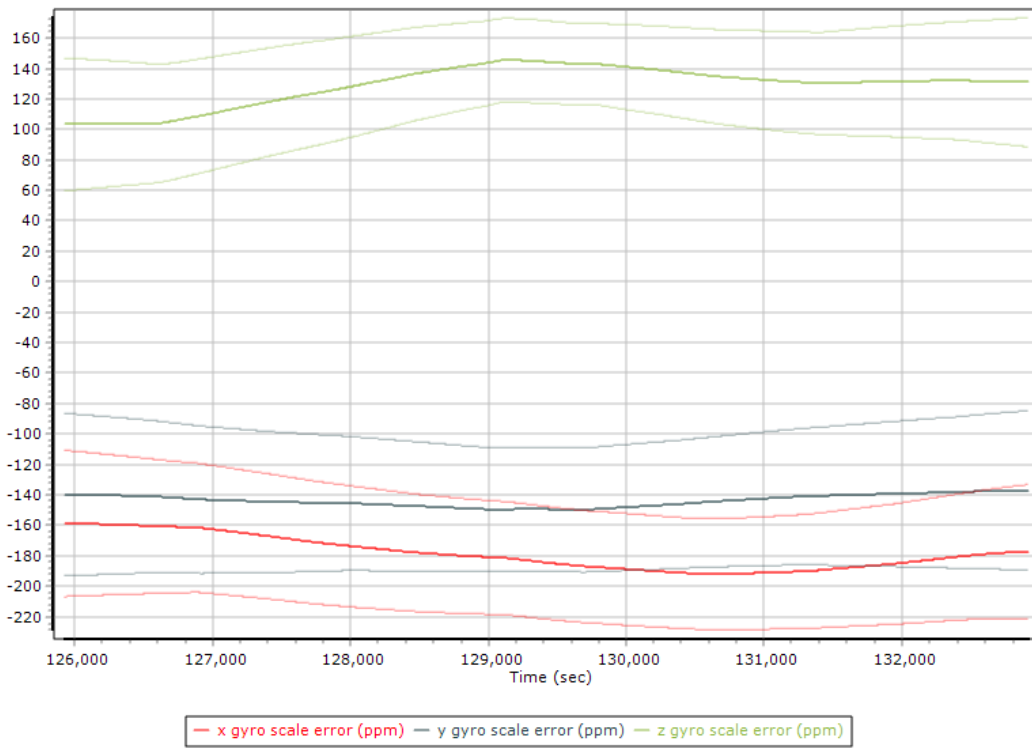
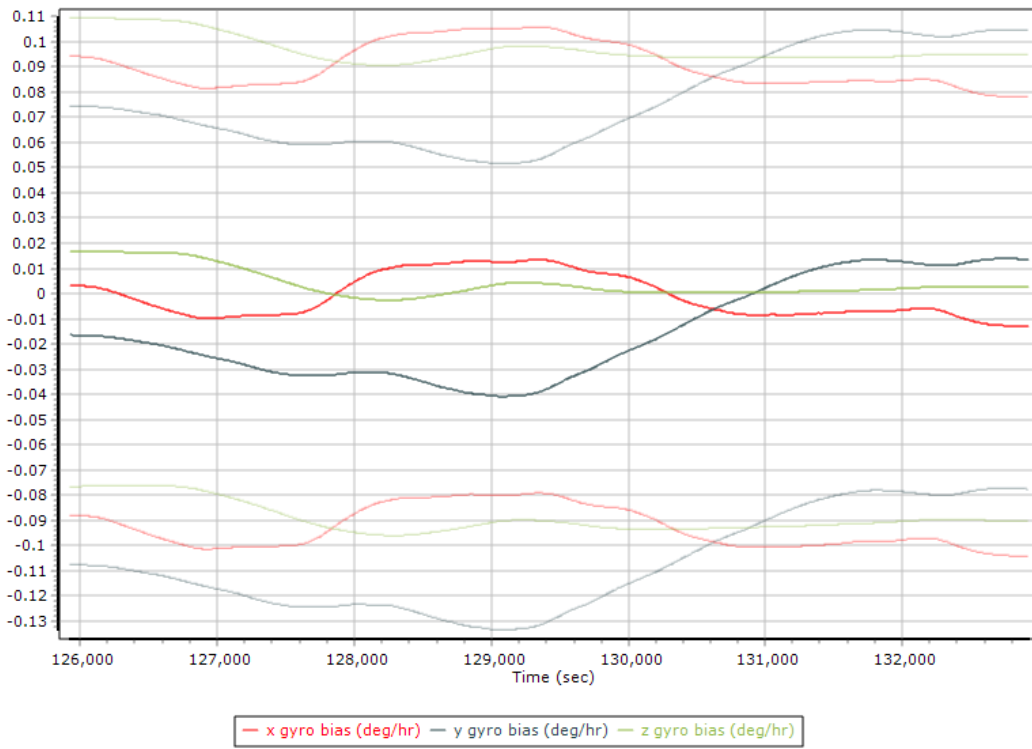


Forward Reverse

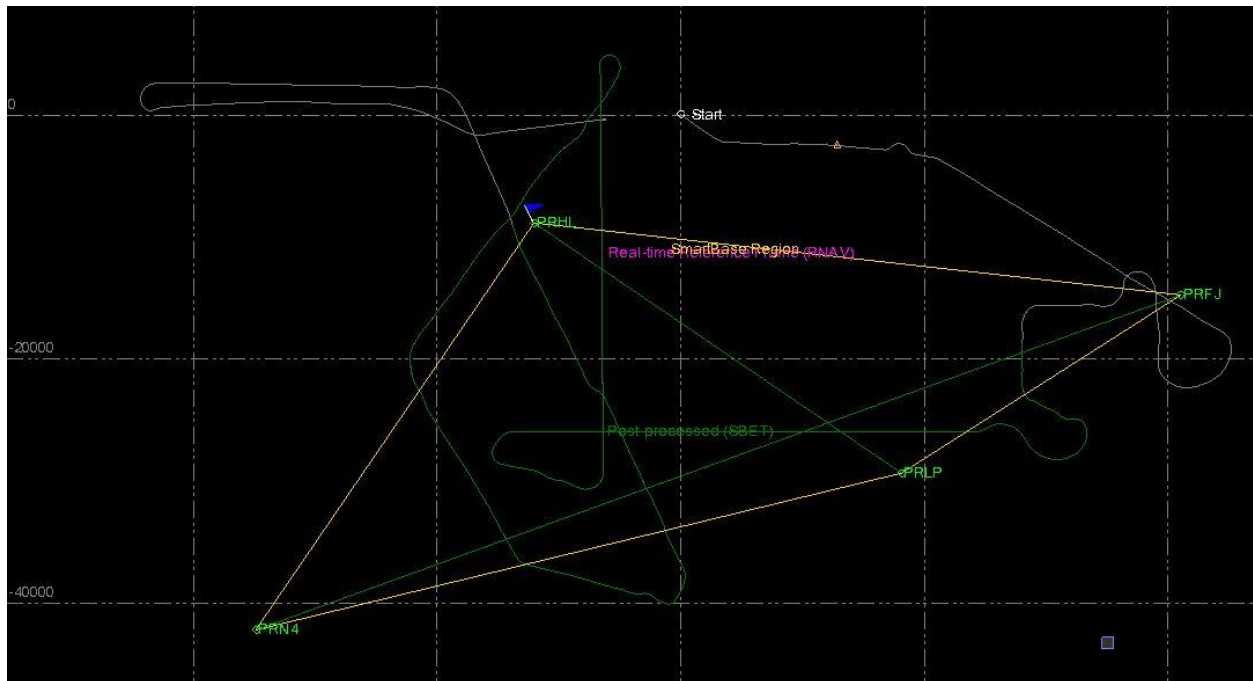
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





RBV18185A



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: -0.037 m	X: 0.000 deg
Y: 0.007 m	Y: 0.000 deg
Z: -0.985 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: 299795.777

End: 303441.633

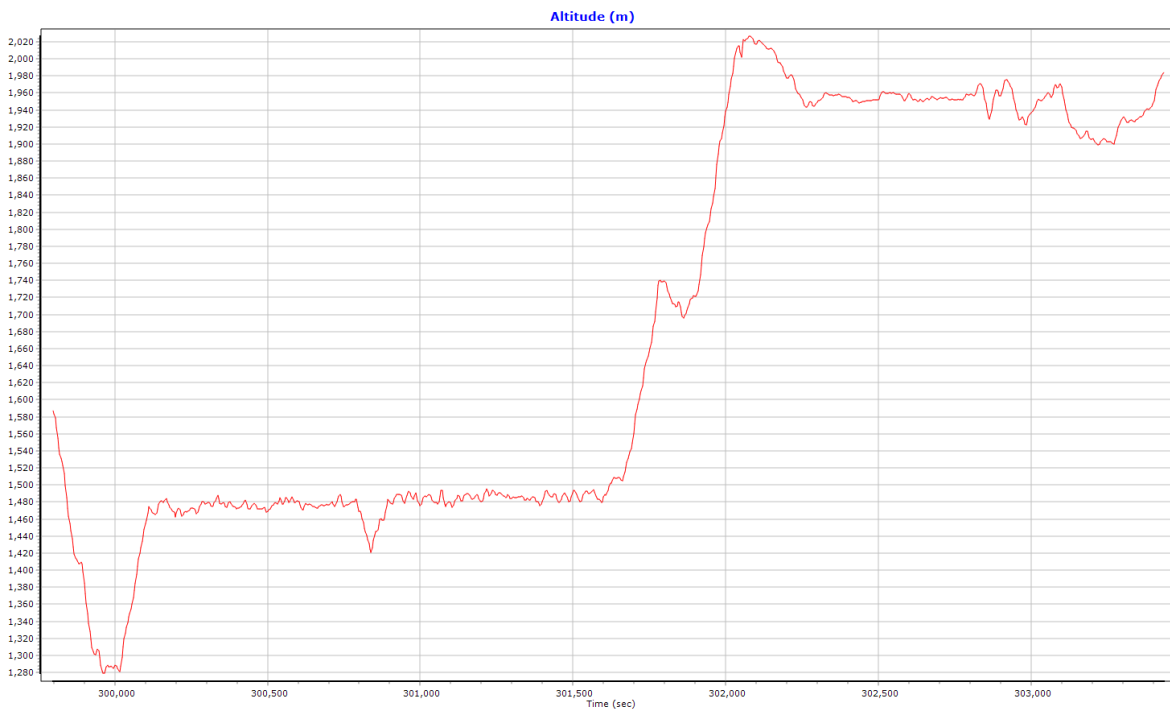
Entire time interval

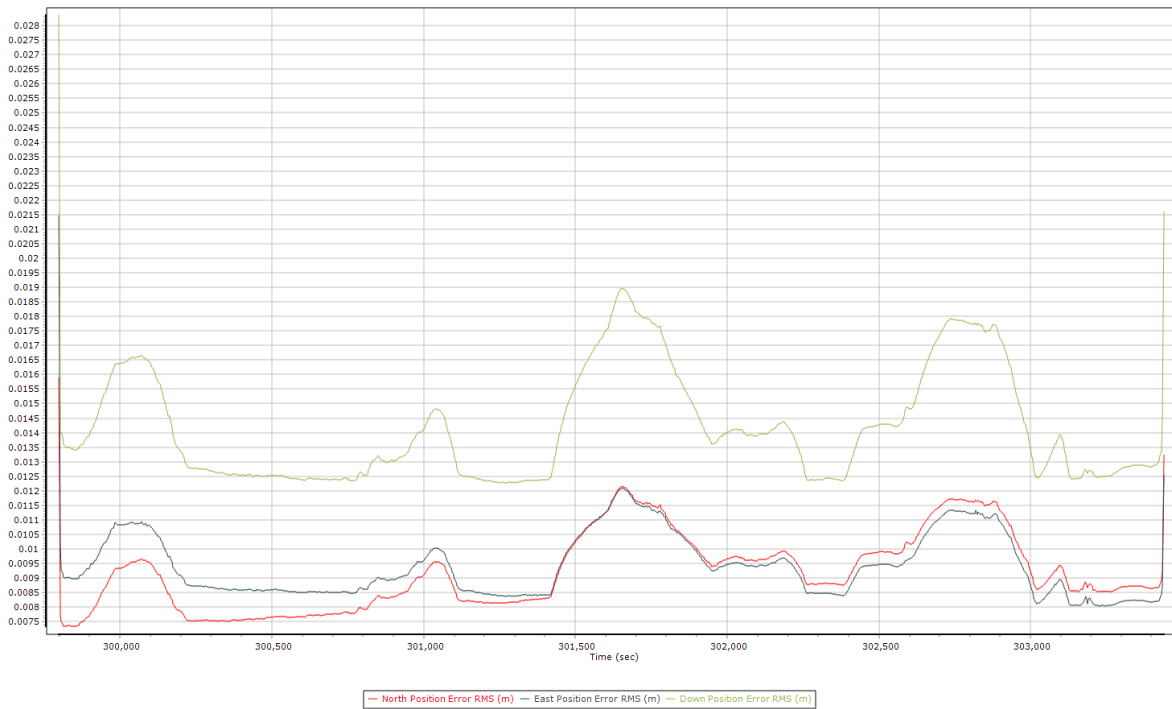
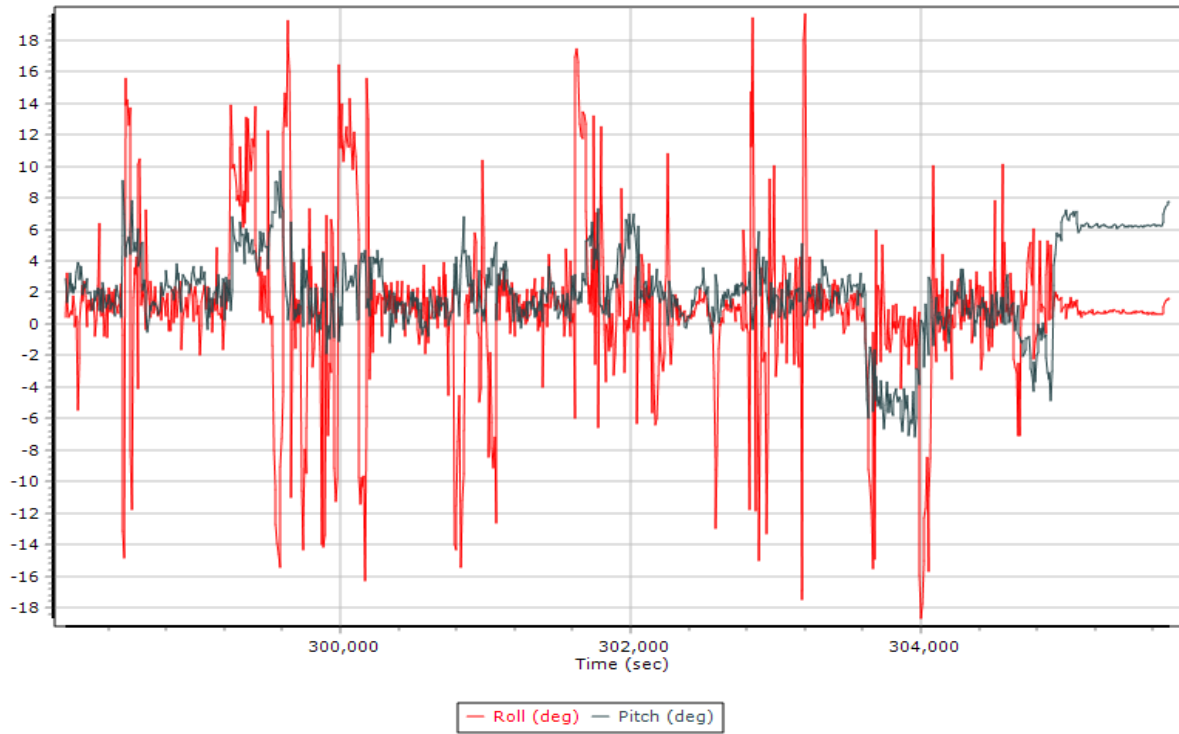
Seconds of start week

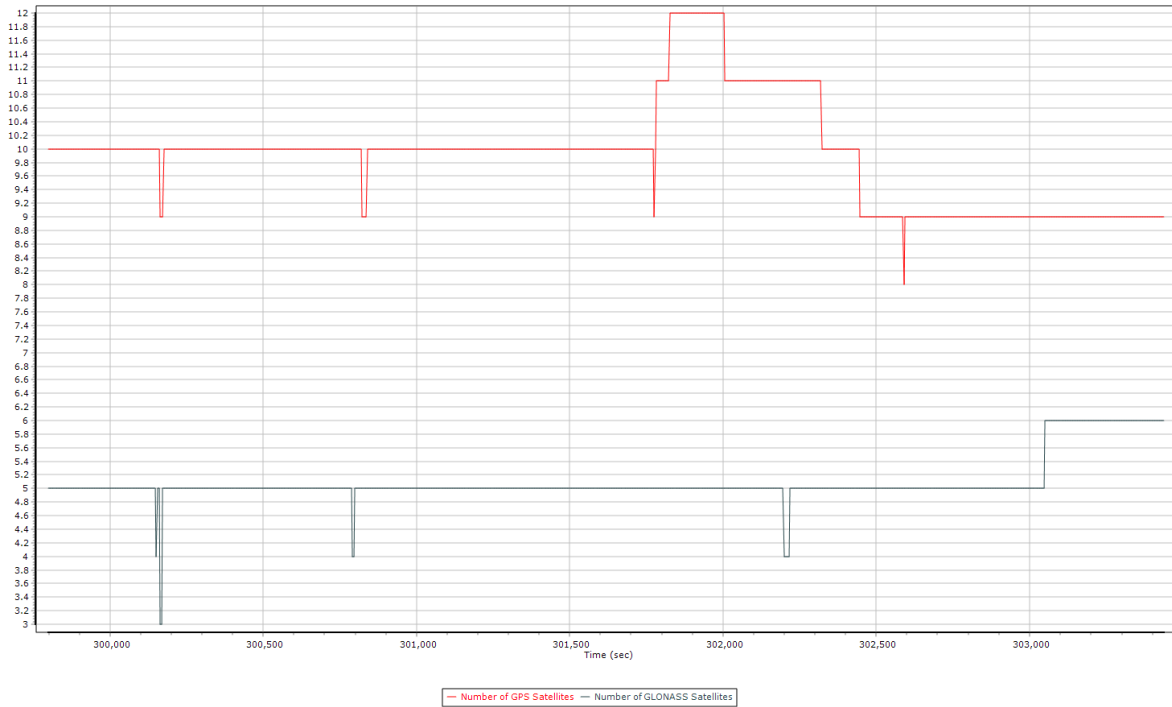
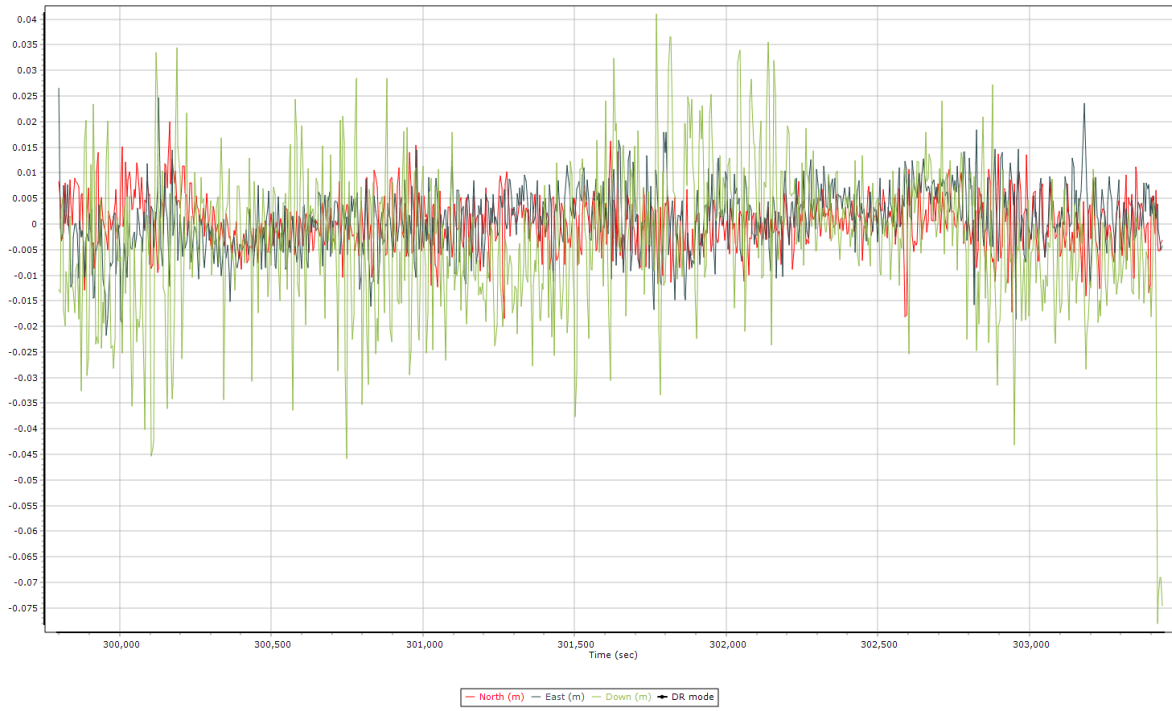
UTC Offset: 18.000

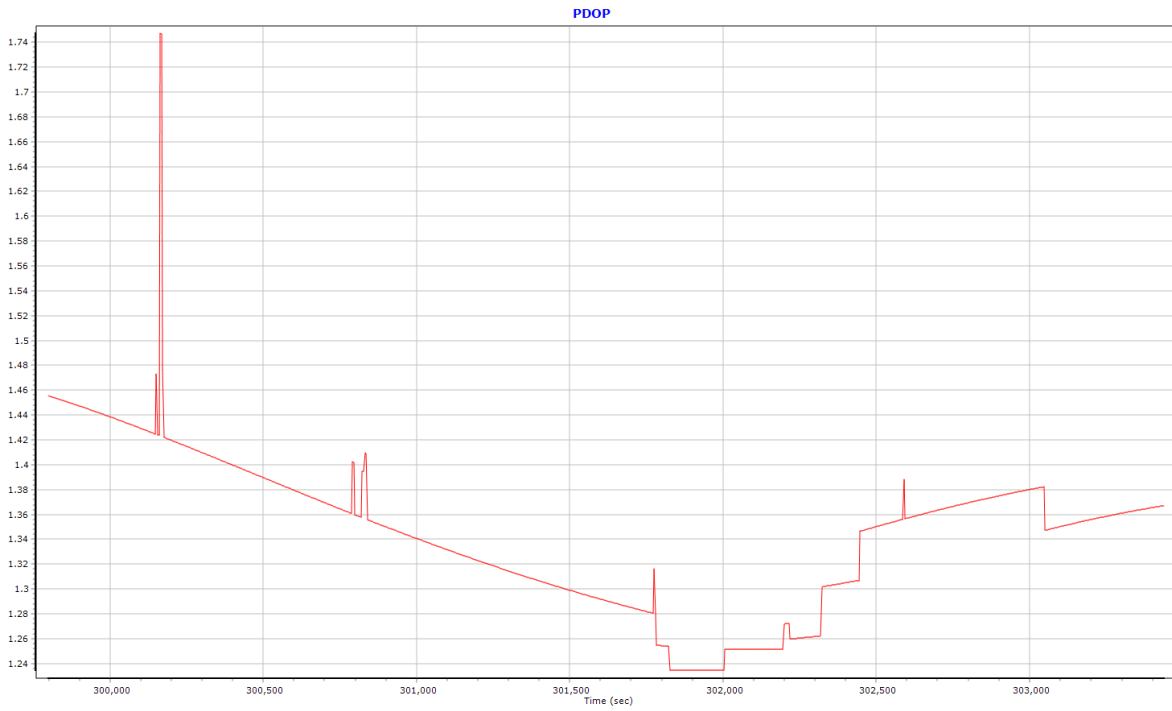
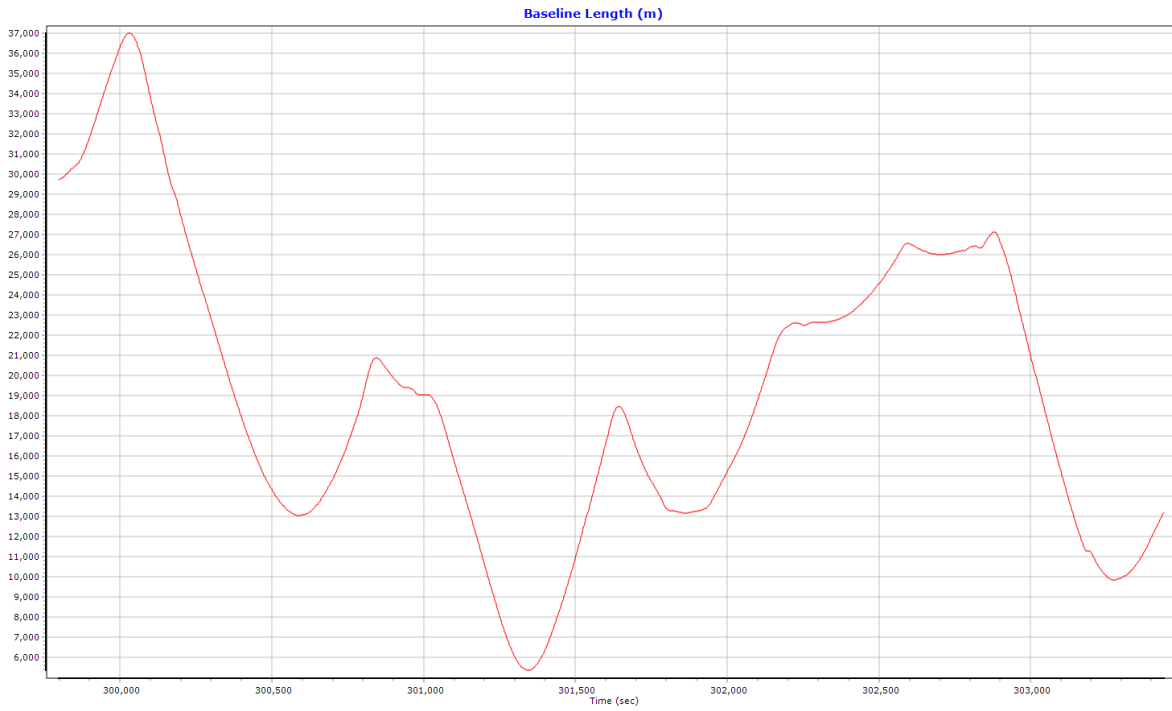
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

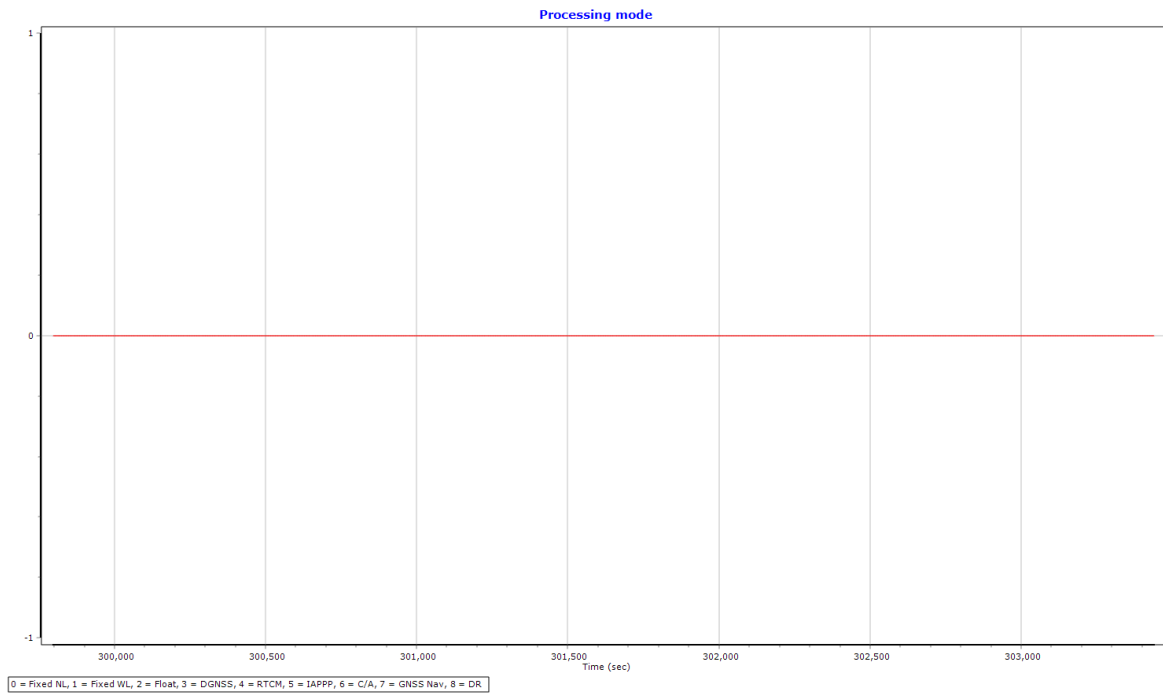
OK Cancel



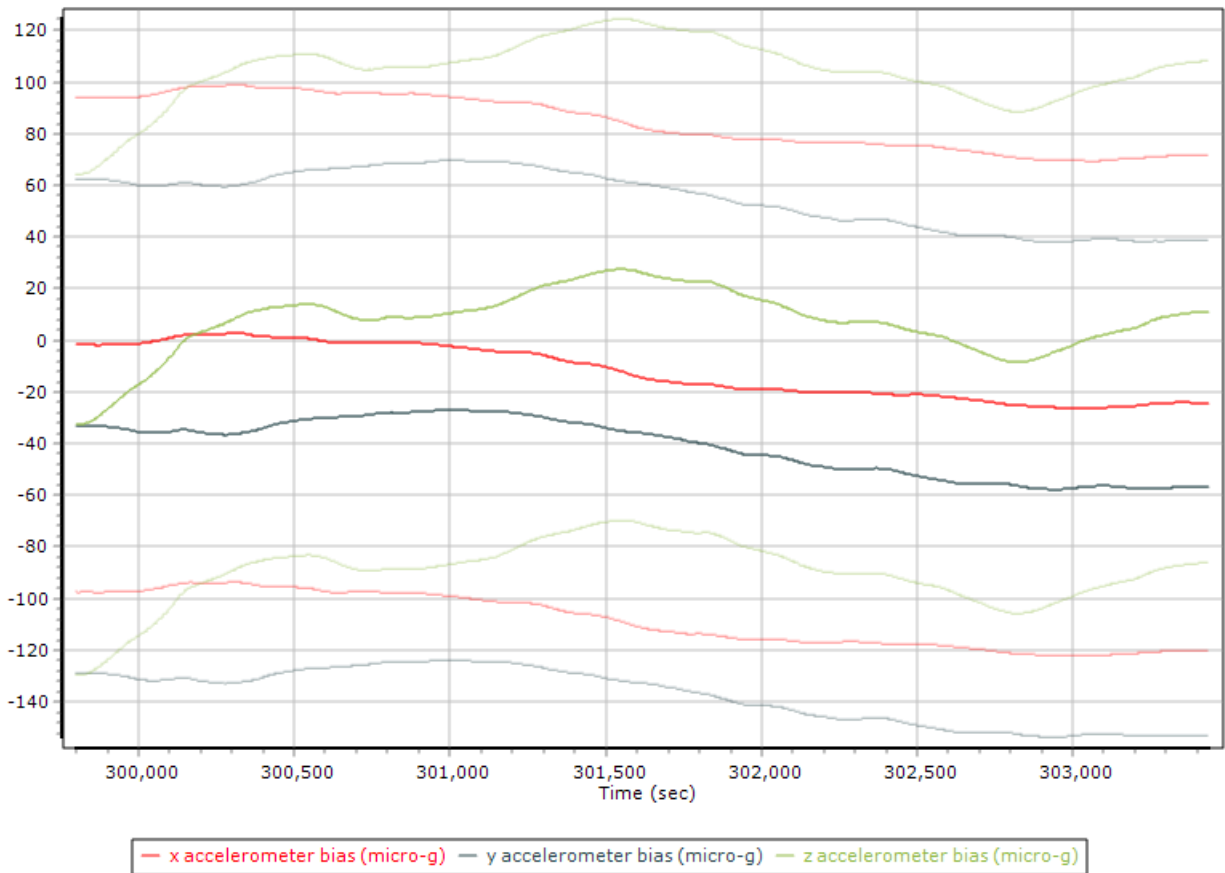


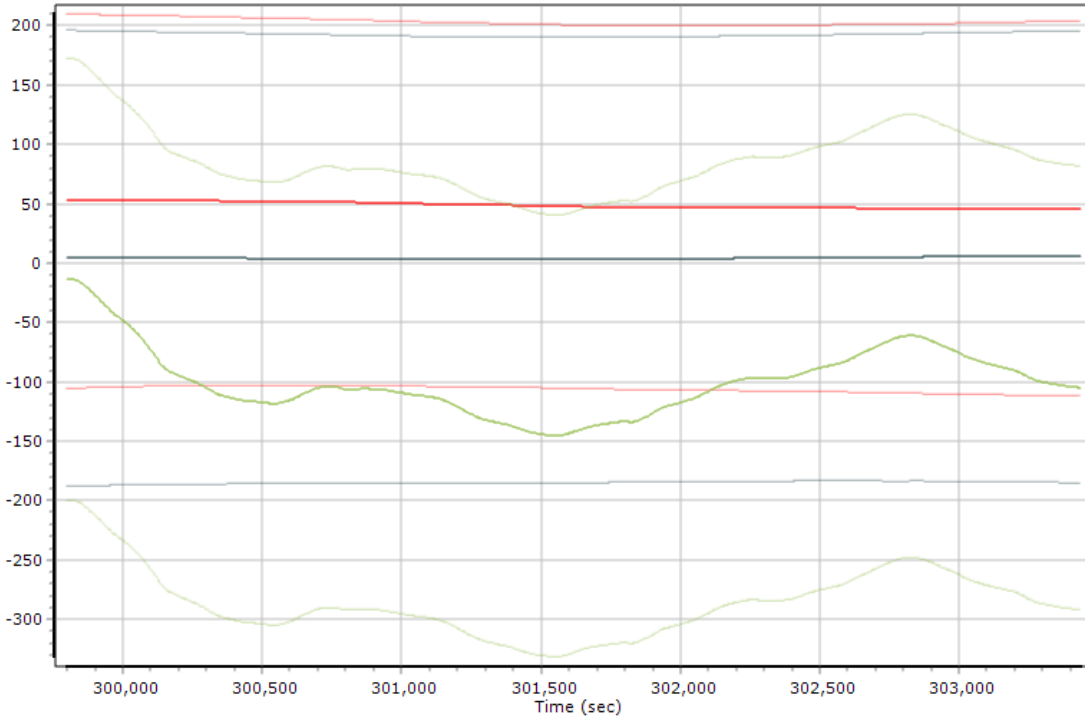




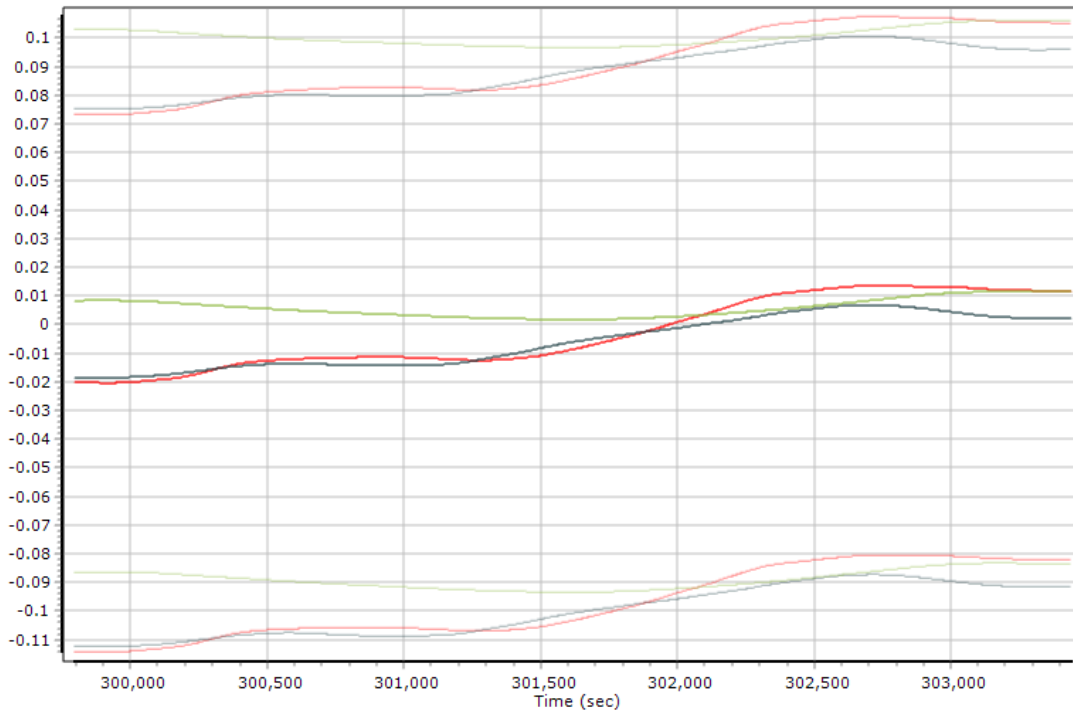


Sensor Errors

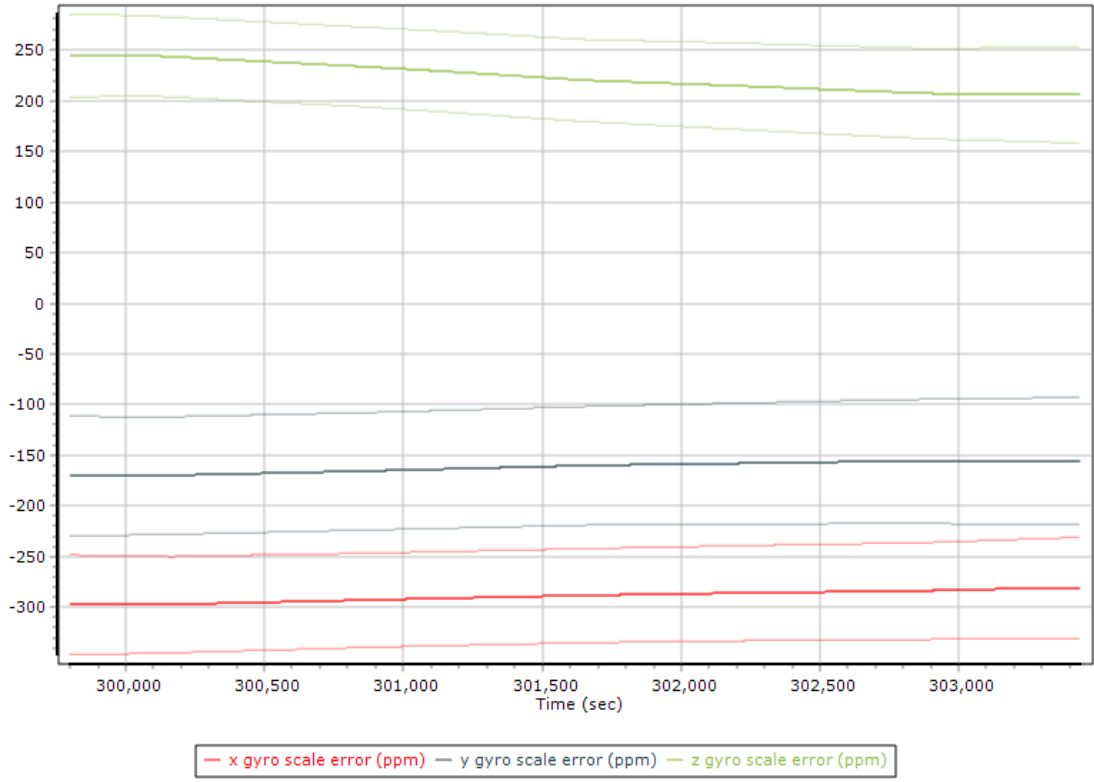




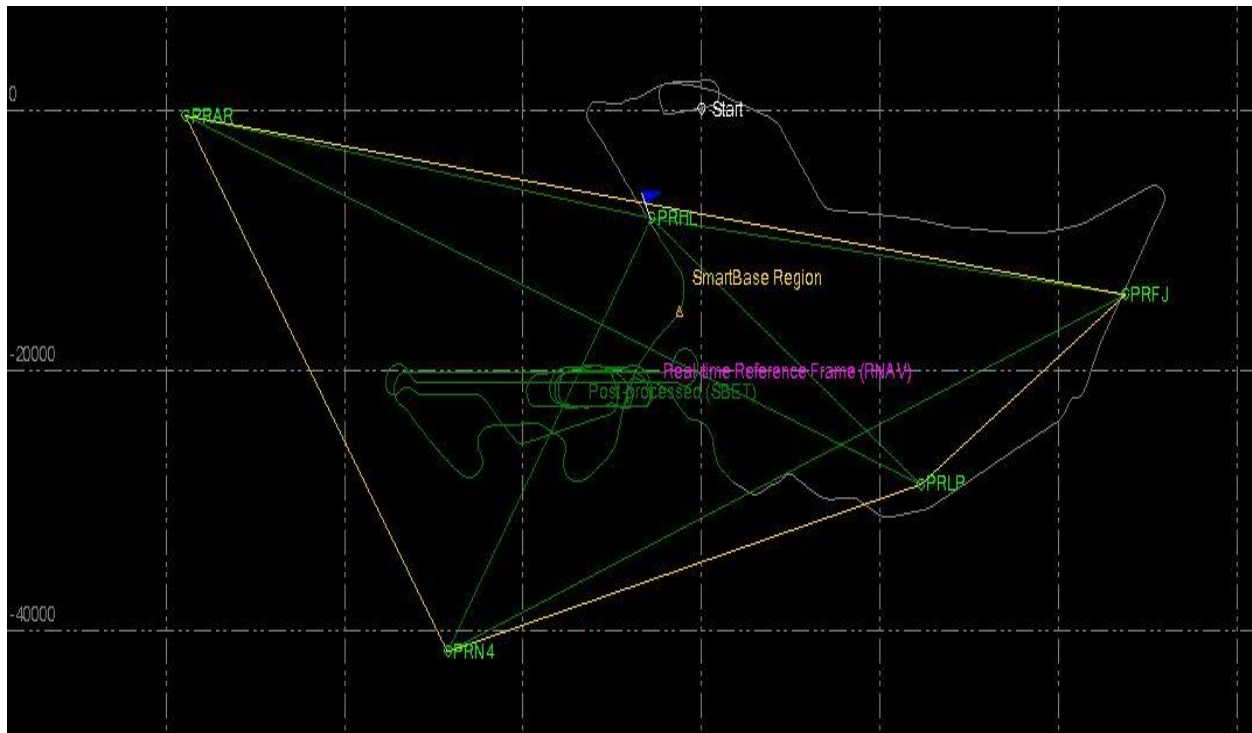
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)

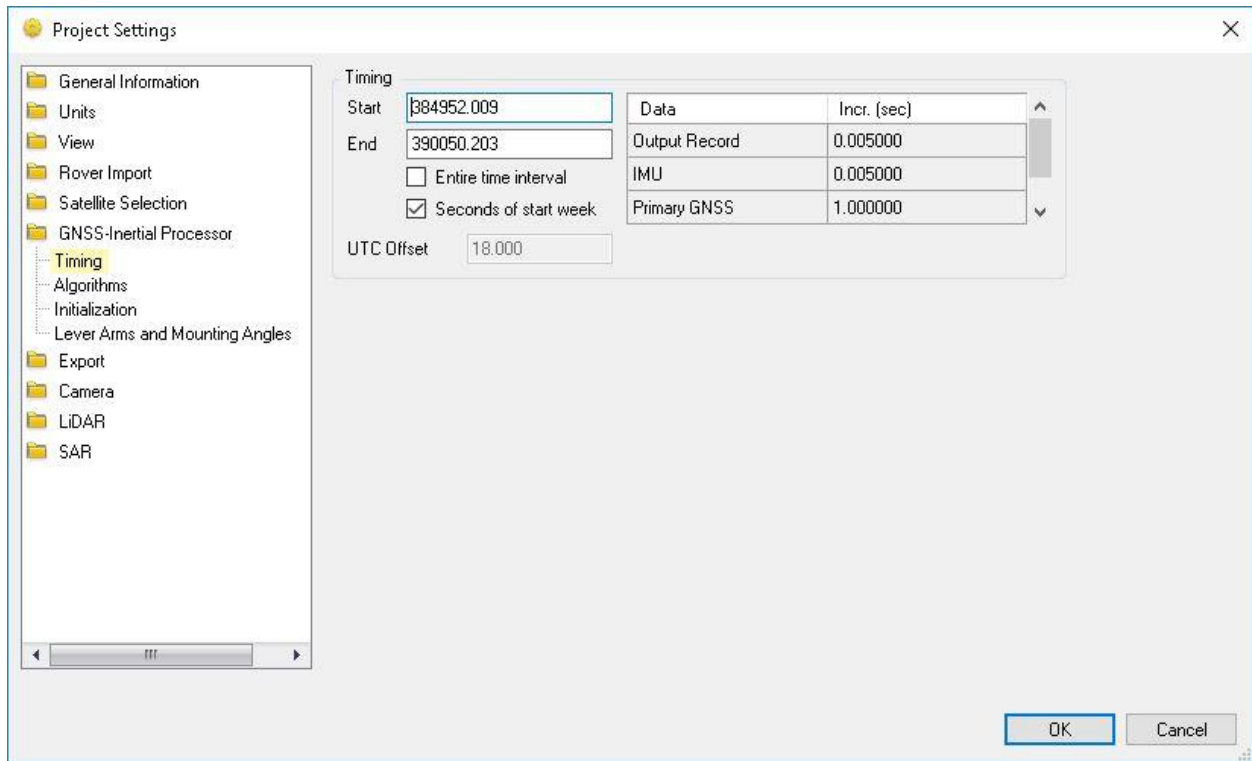
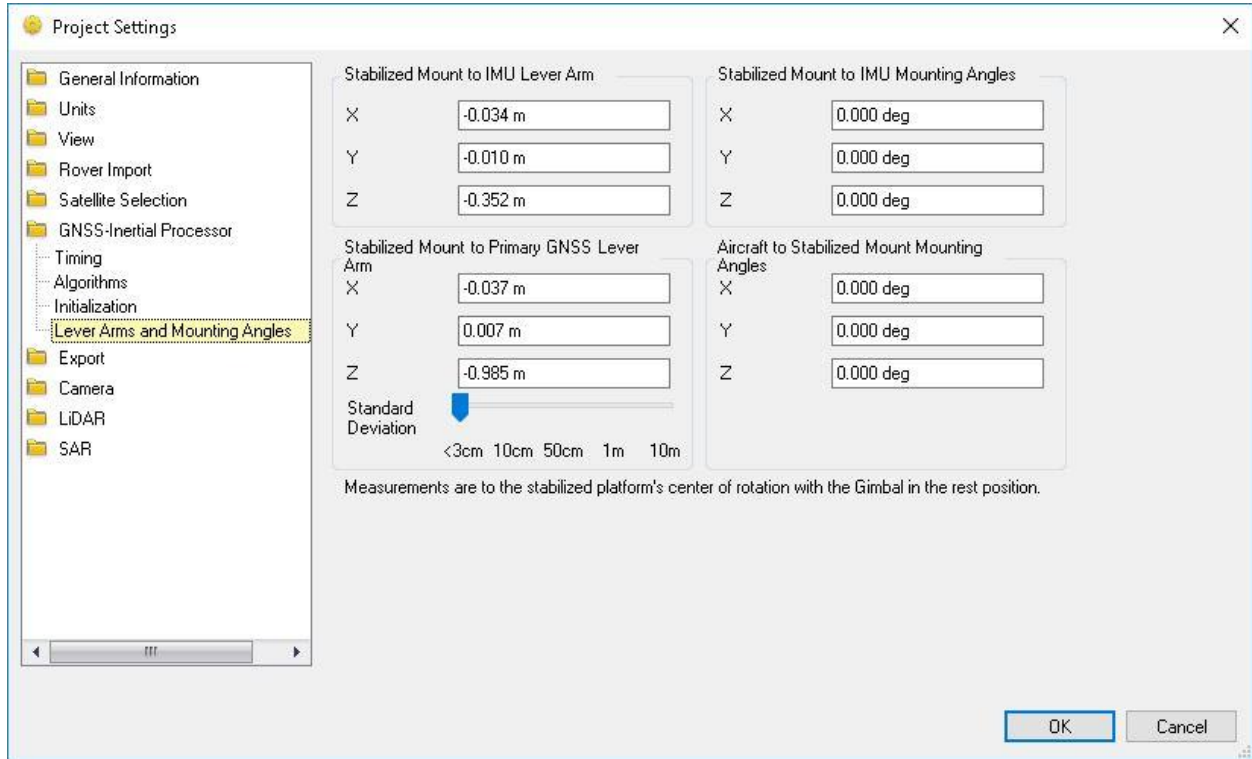


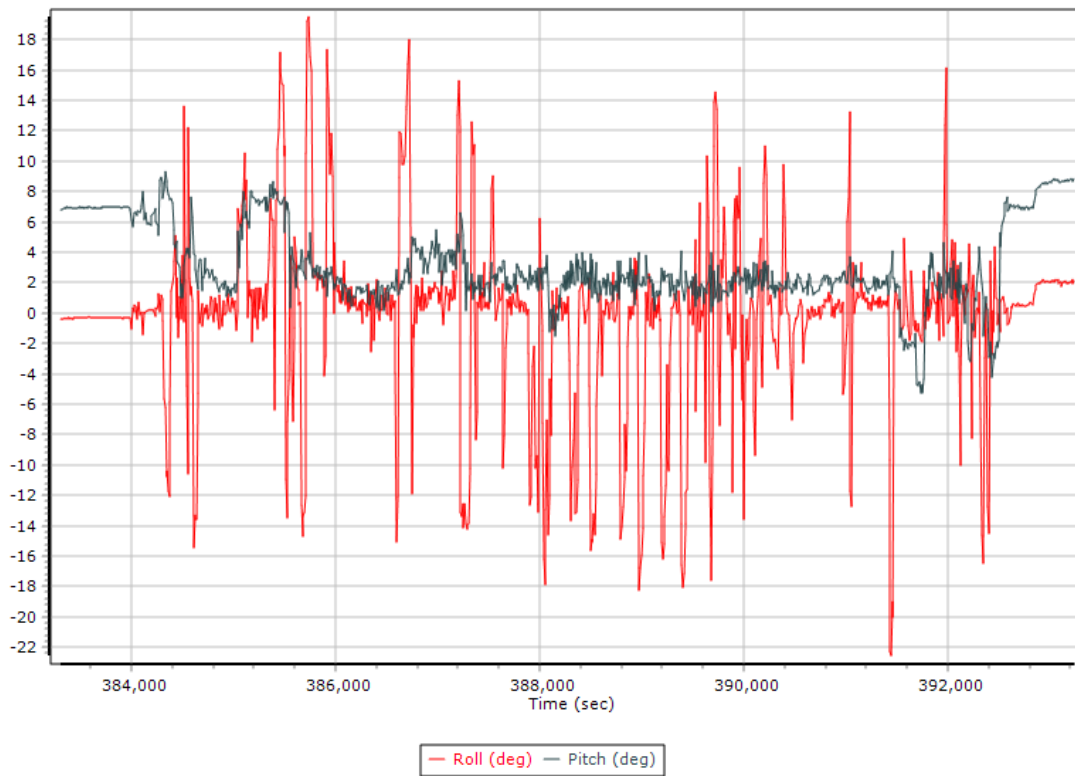
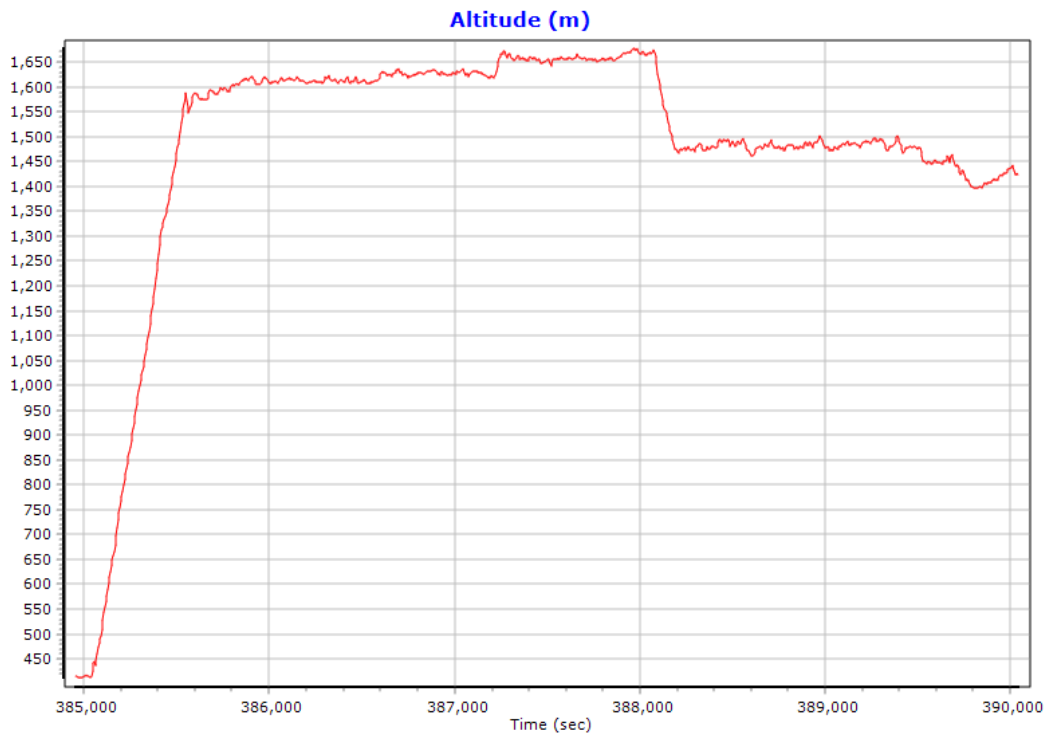
— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

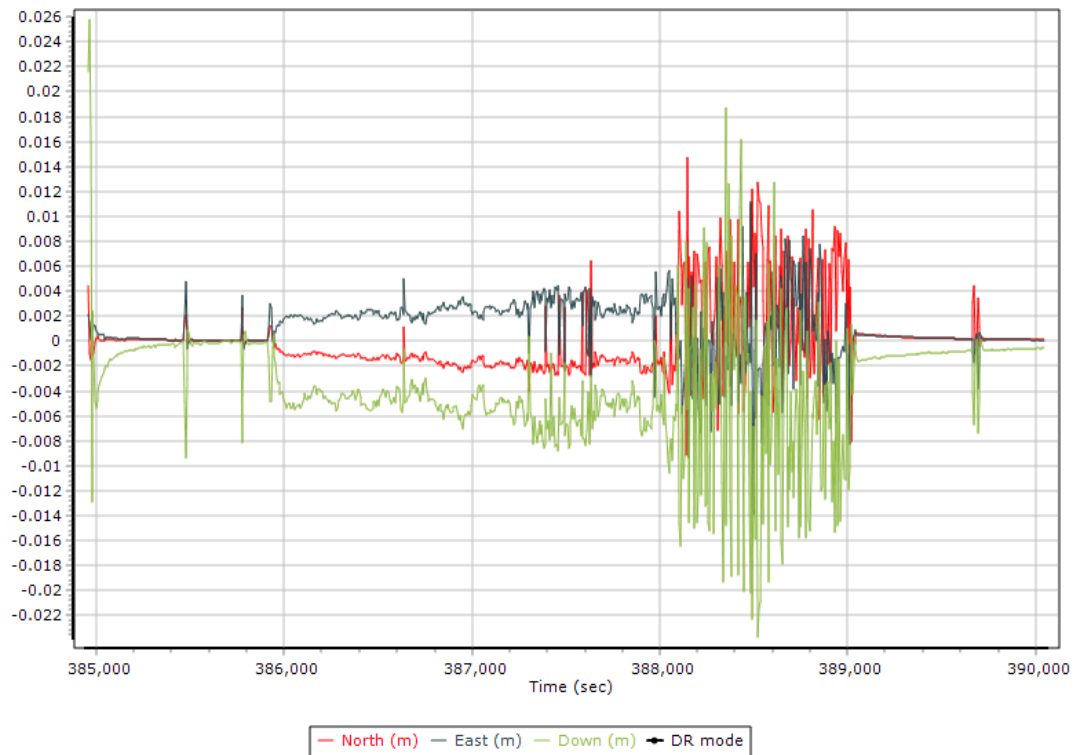
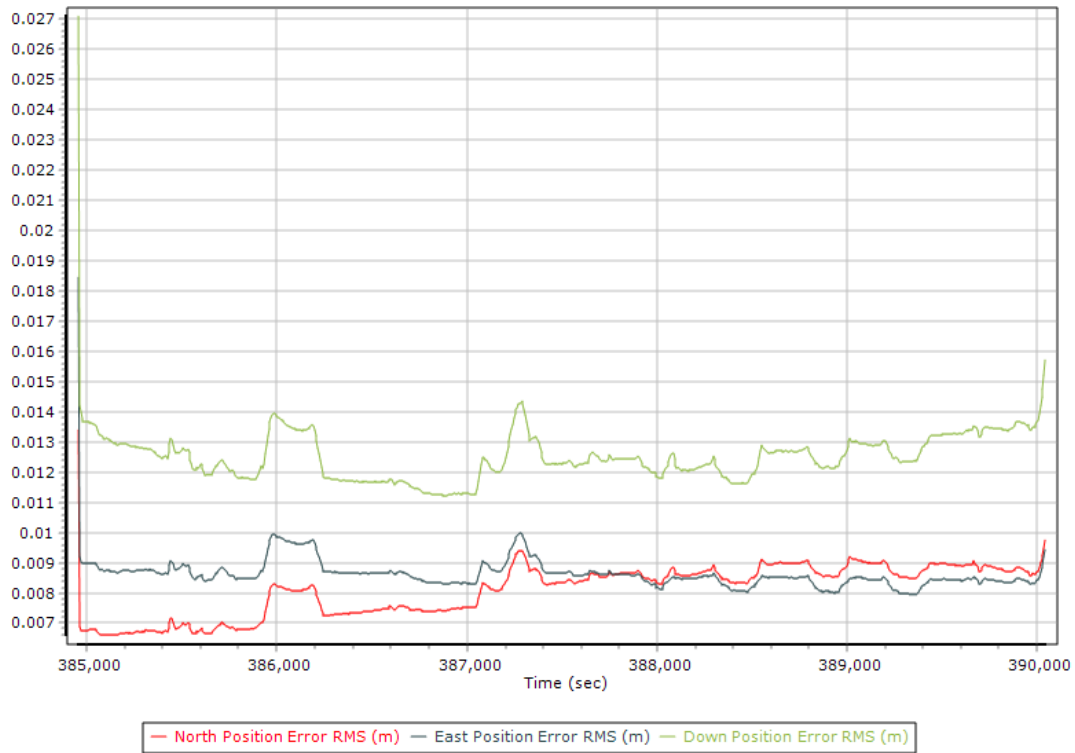


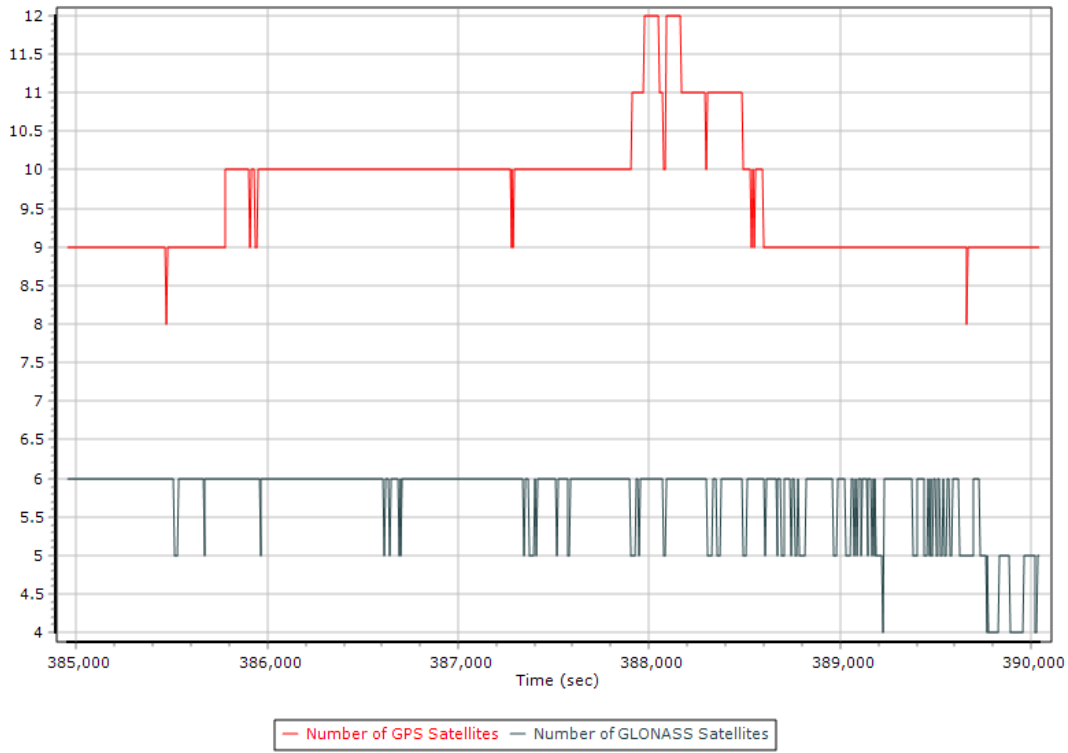
RBV18186A



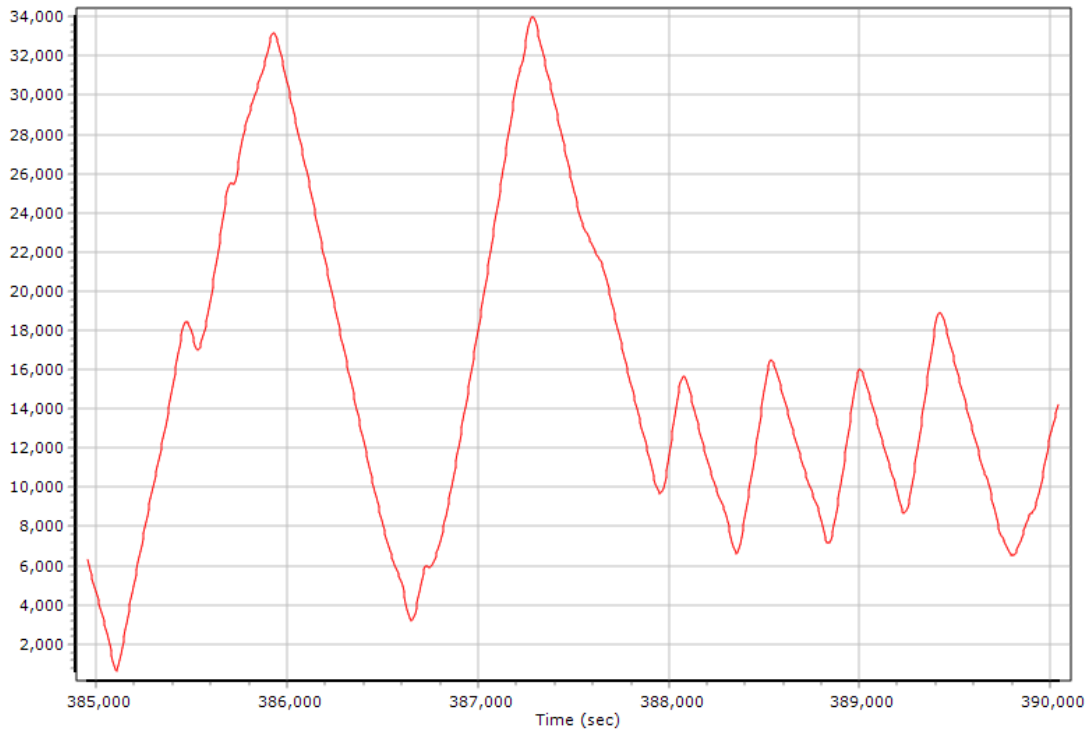




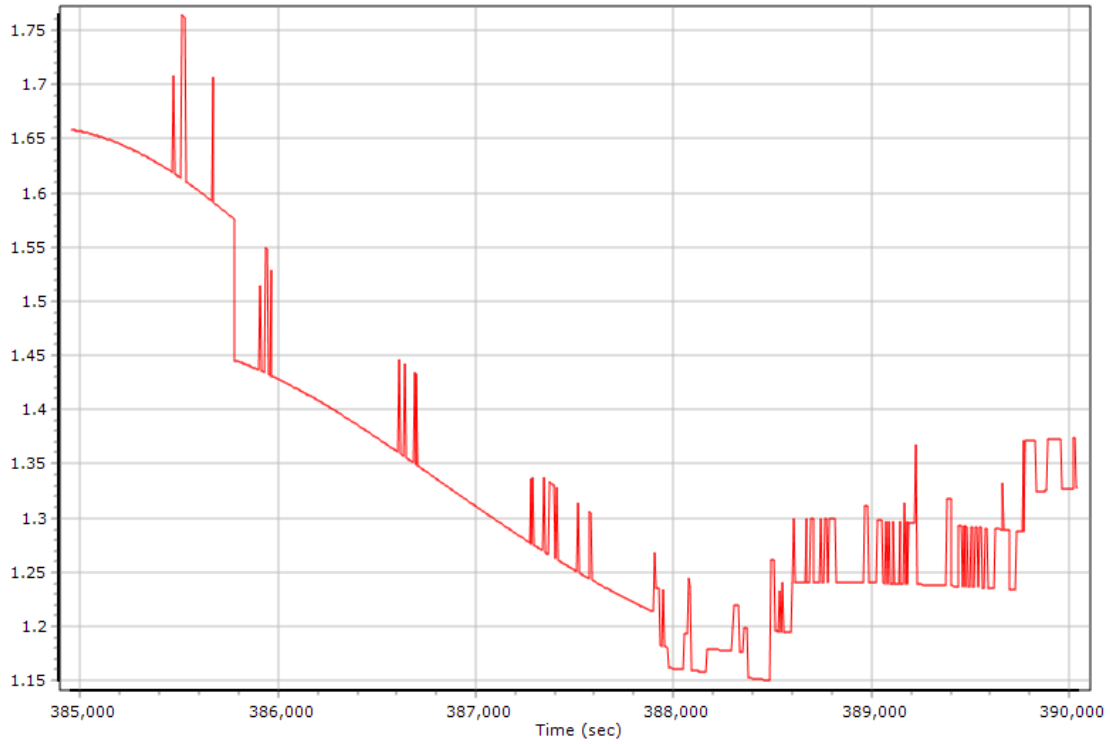




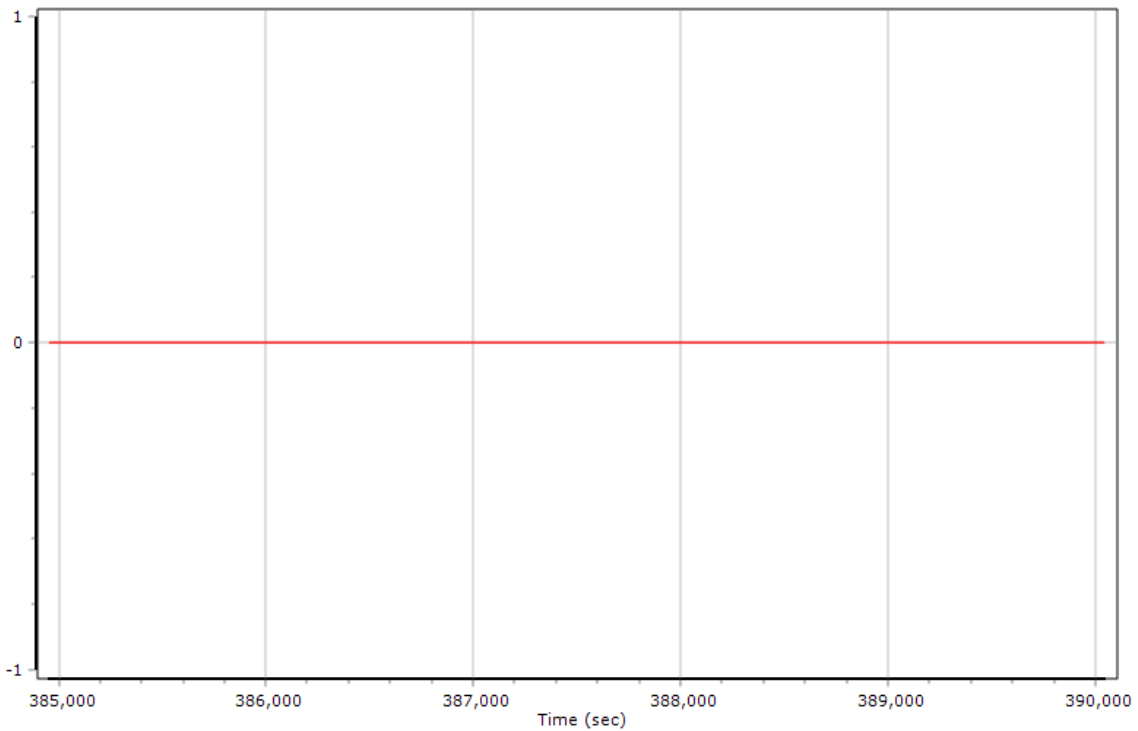
Baseline Length (m)



PDOP

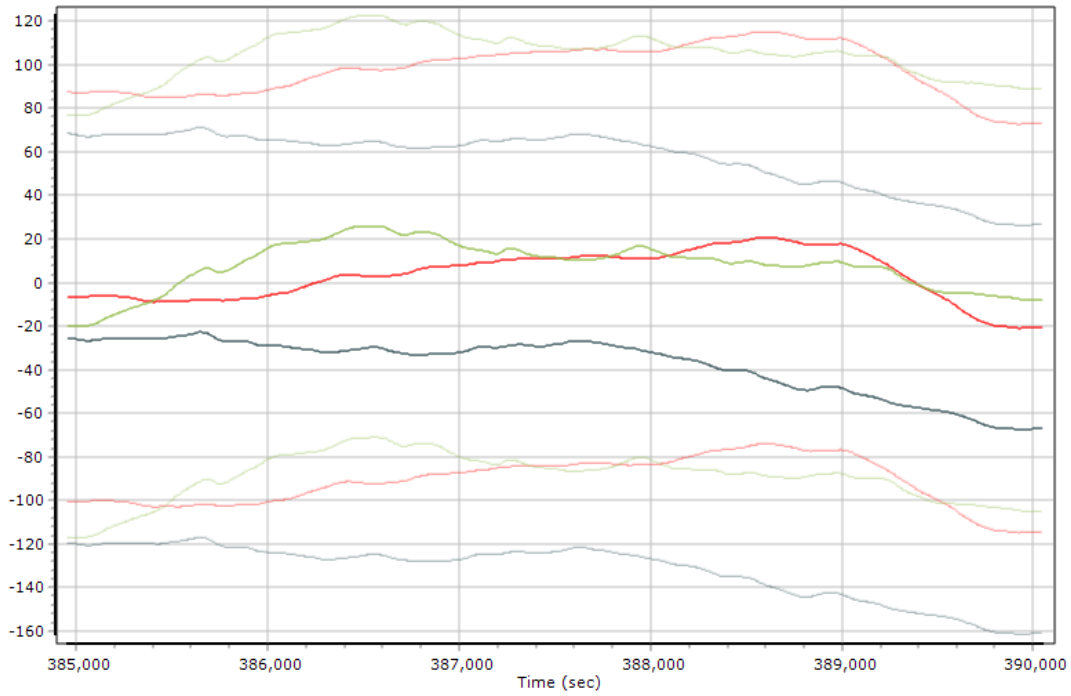


Processing mode

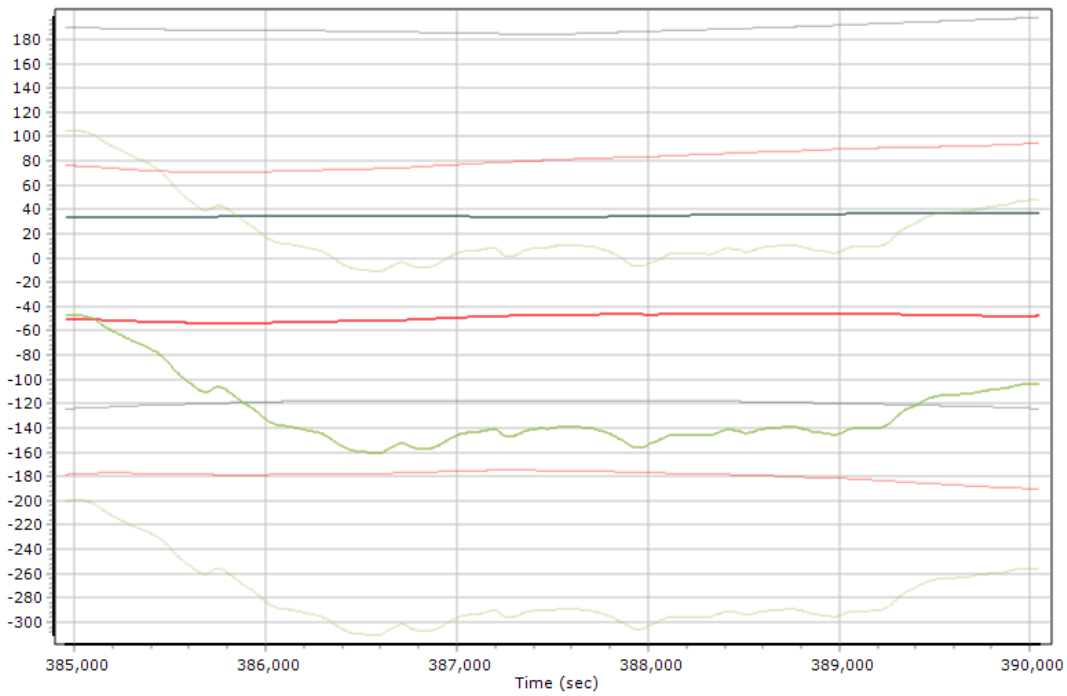


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

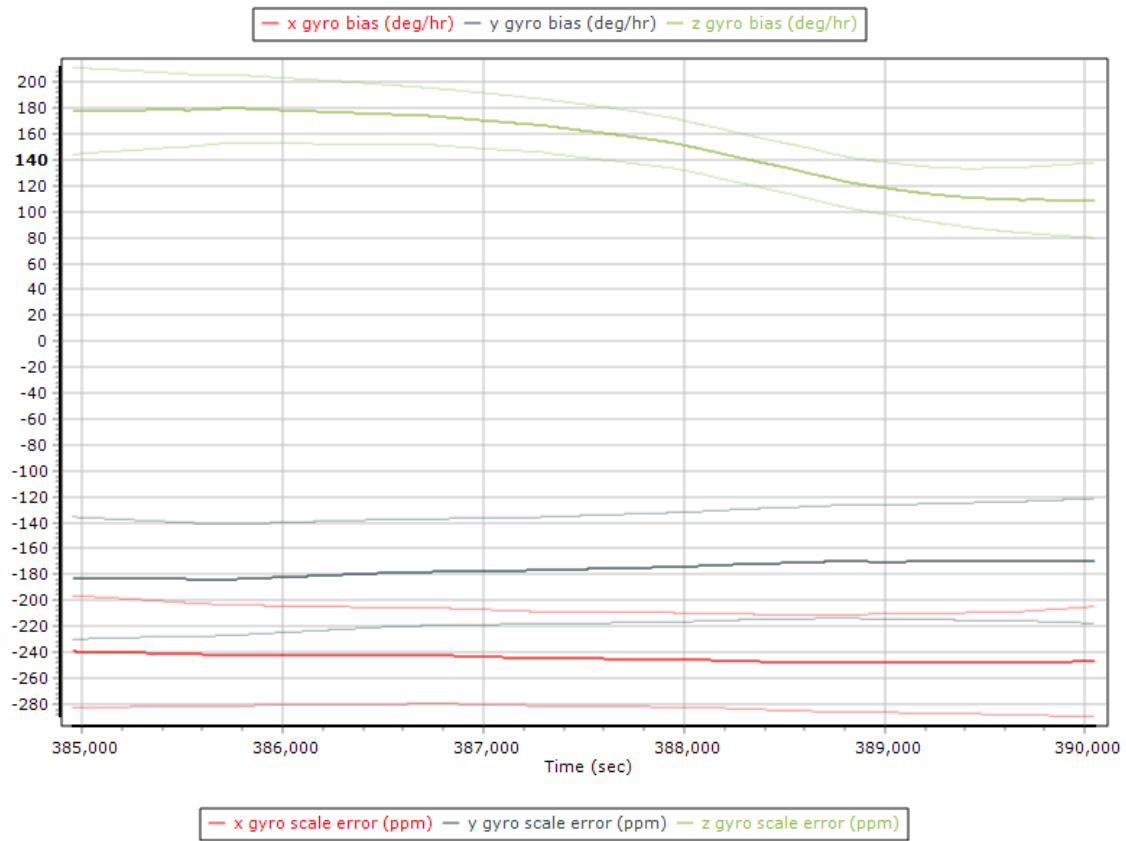
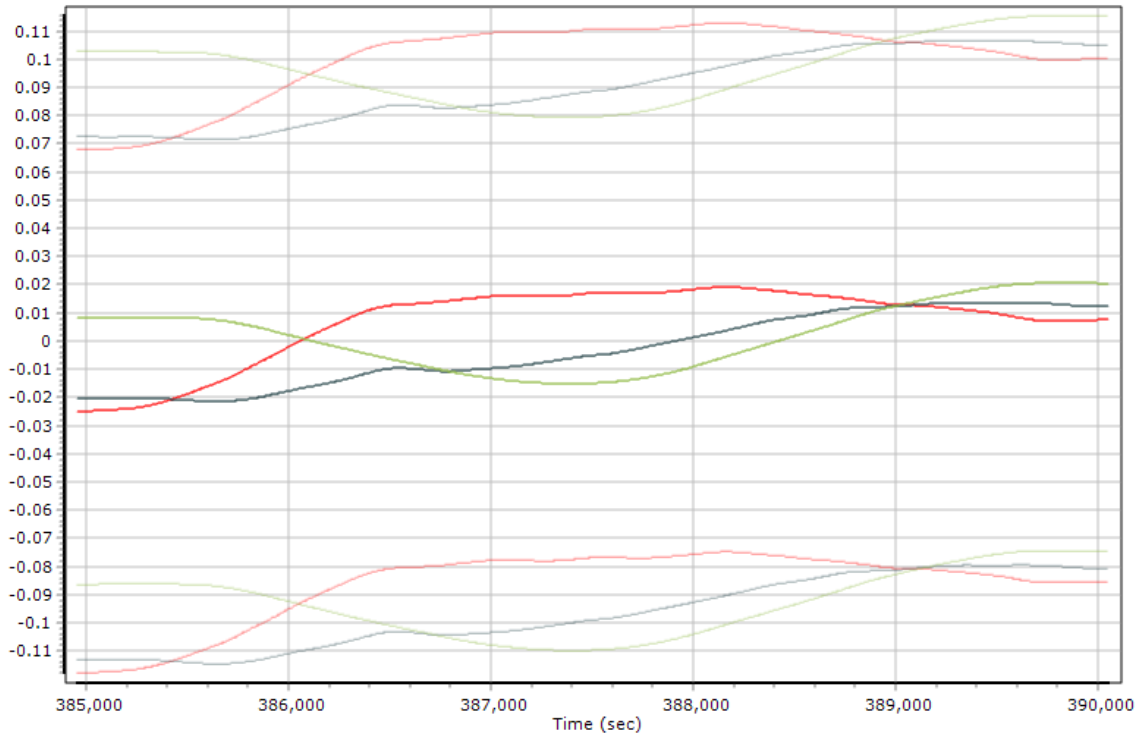
Sensor Errors



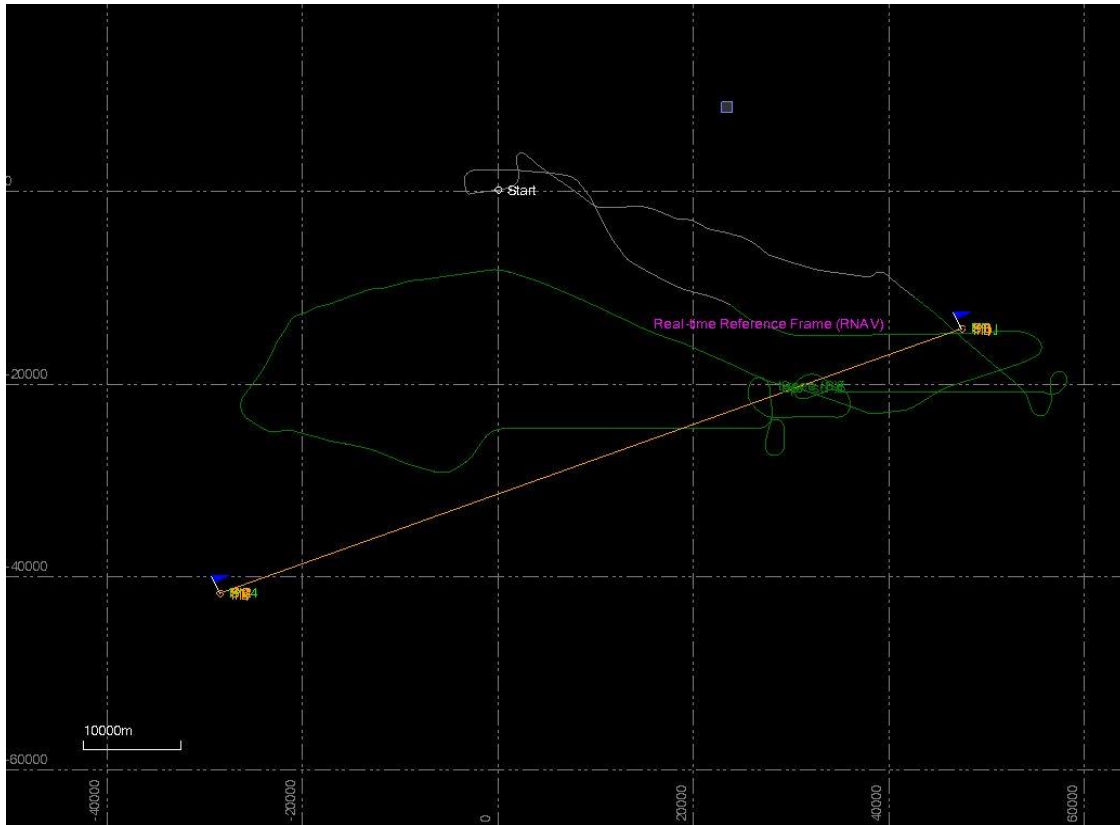
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)



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



RBV18193A



Project Settings

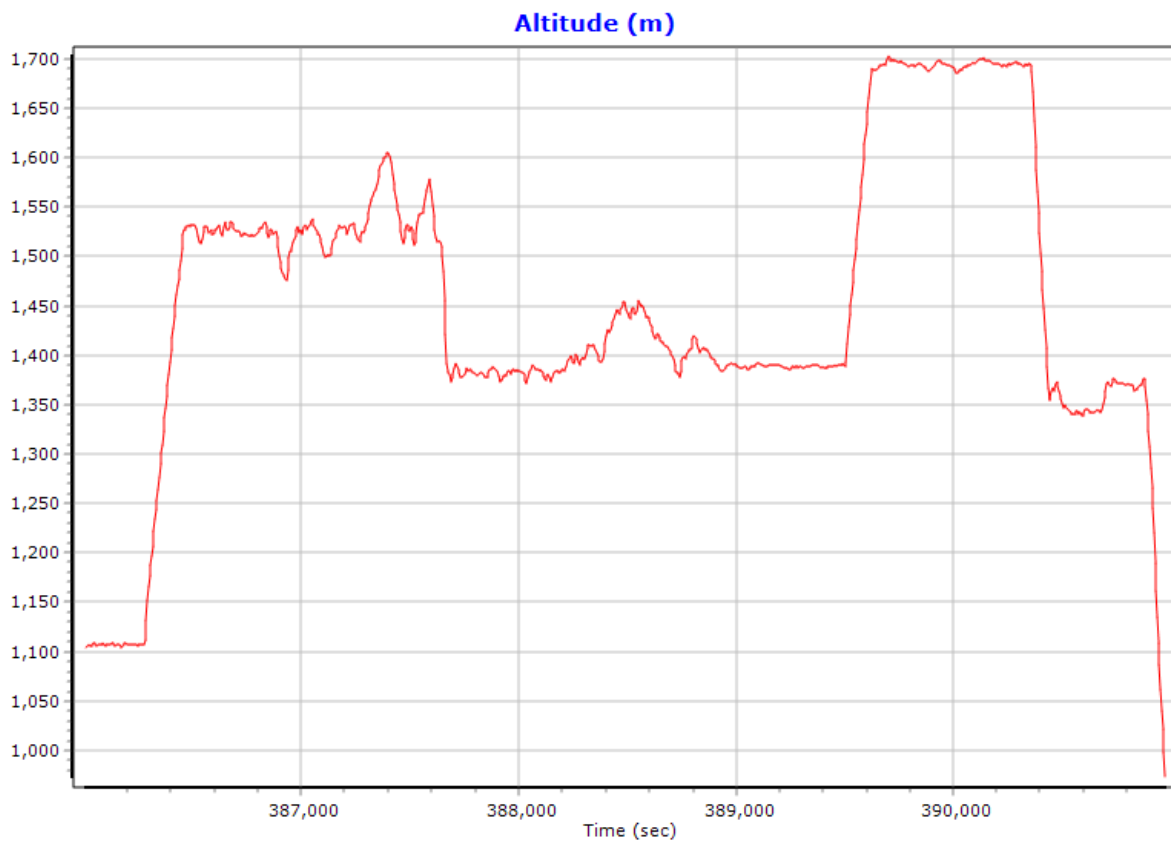
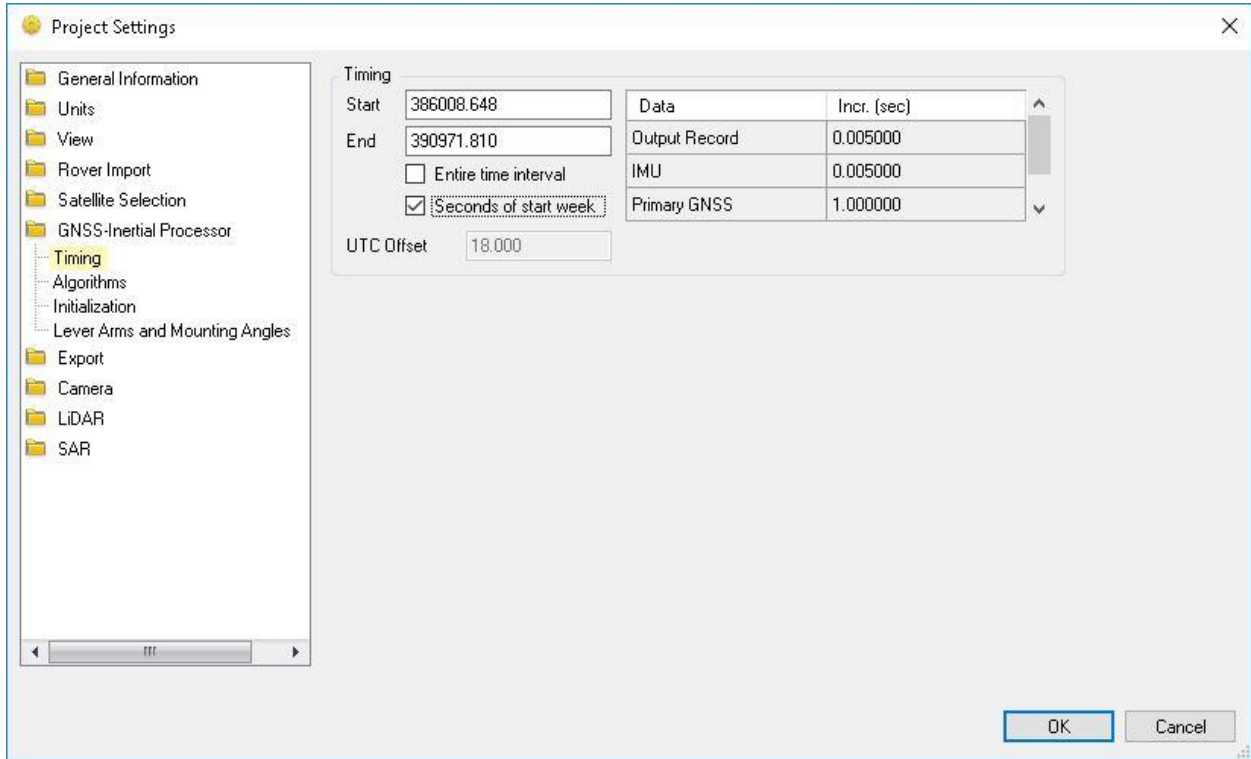
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

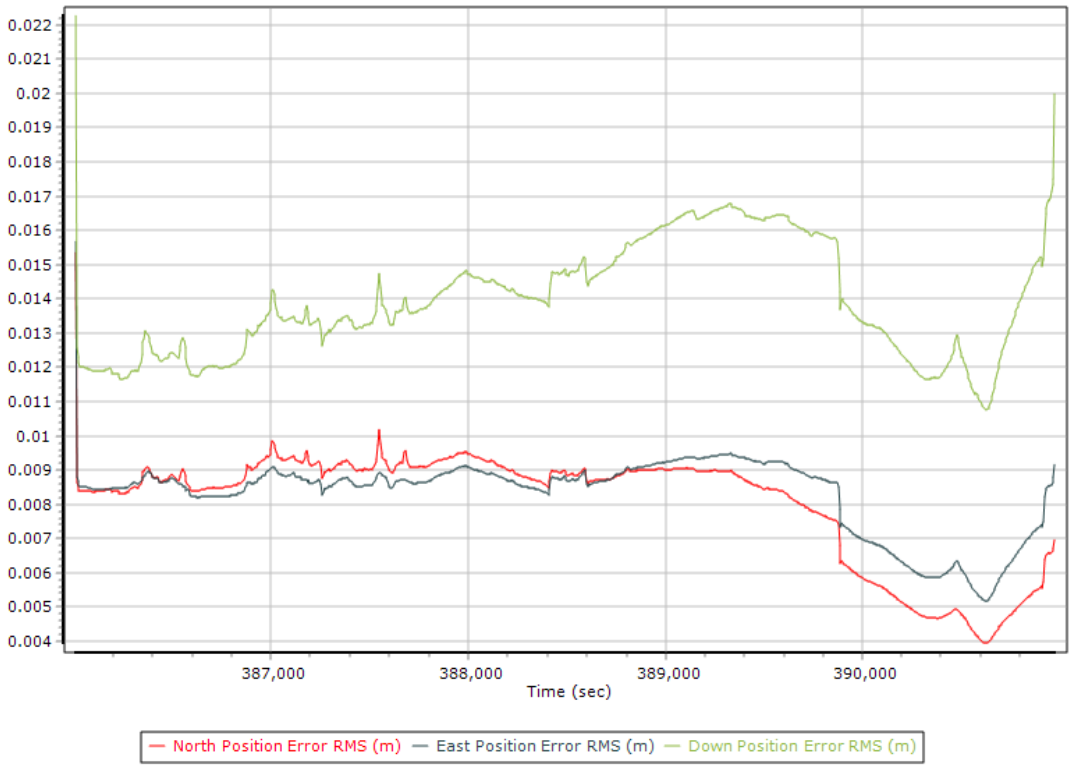
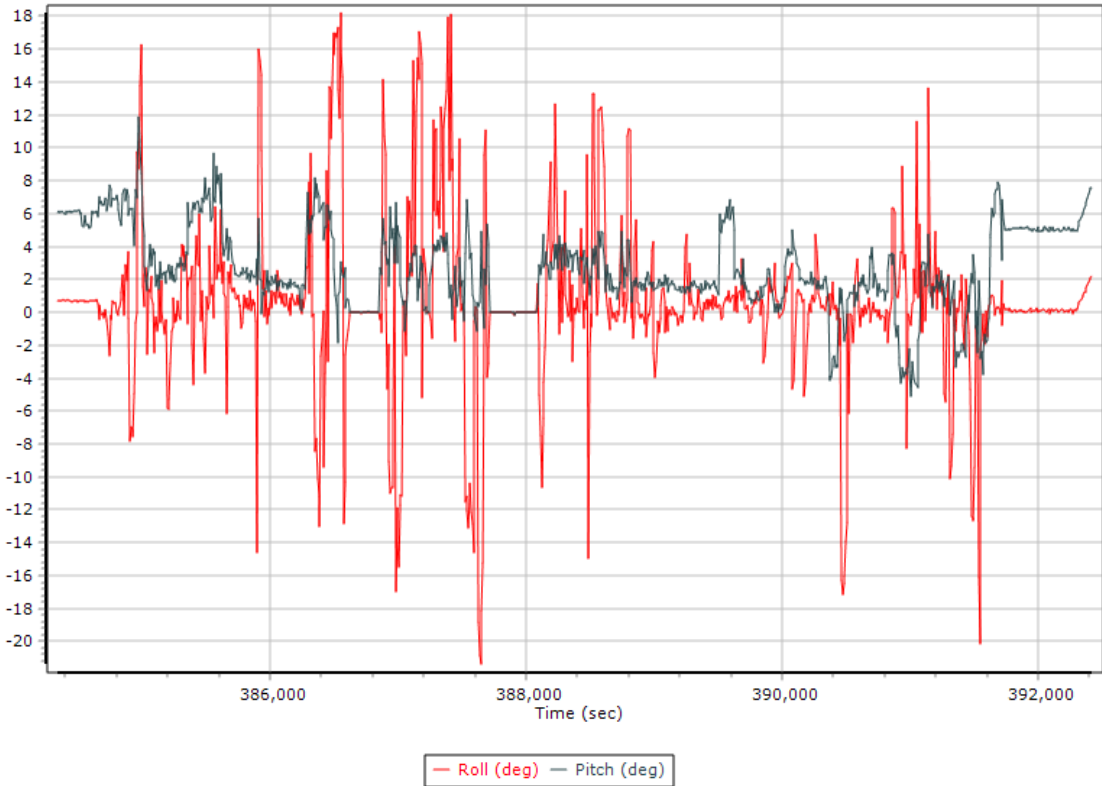
Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	-0.034 m	-0.010 m	-0.352 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.037 m	0.007 m	-0.985 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

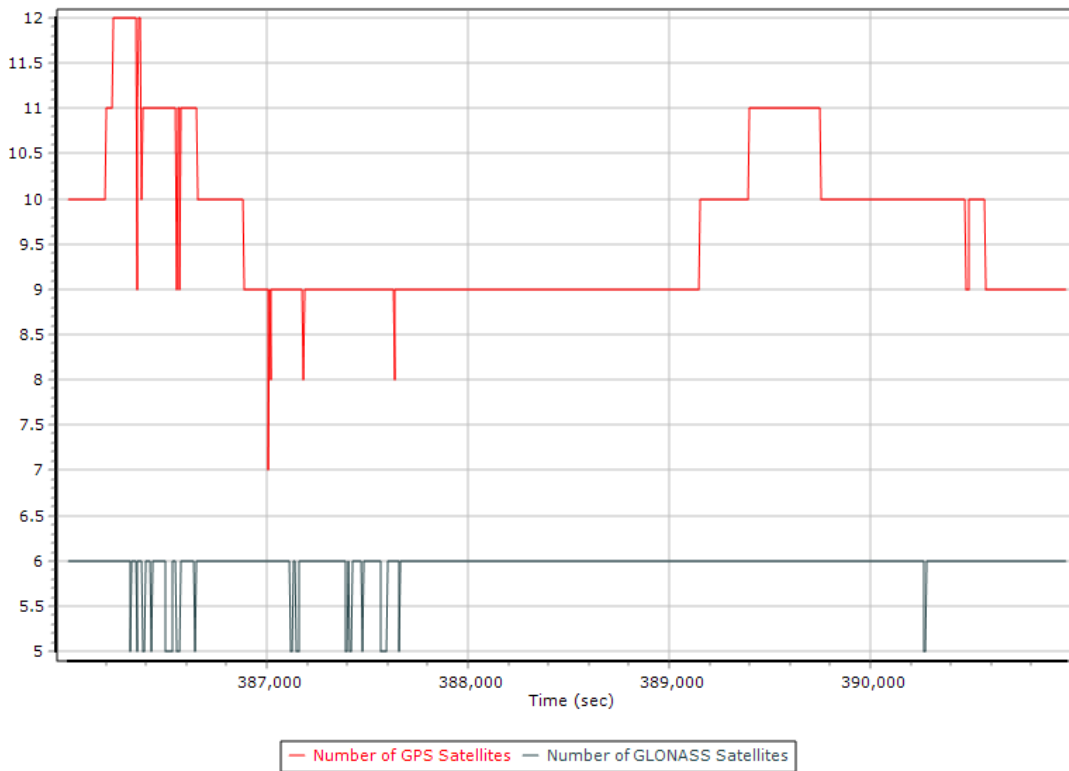
Standard Deviation: <3cm 10cm 50cm 1m 10m

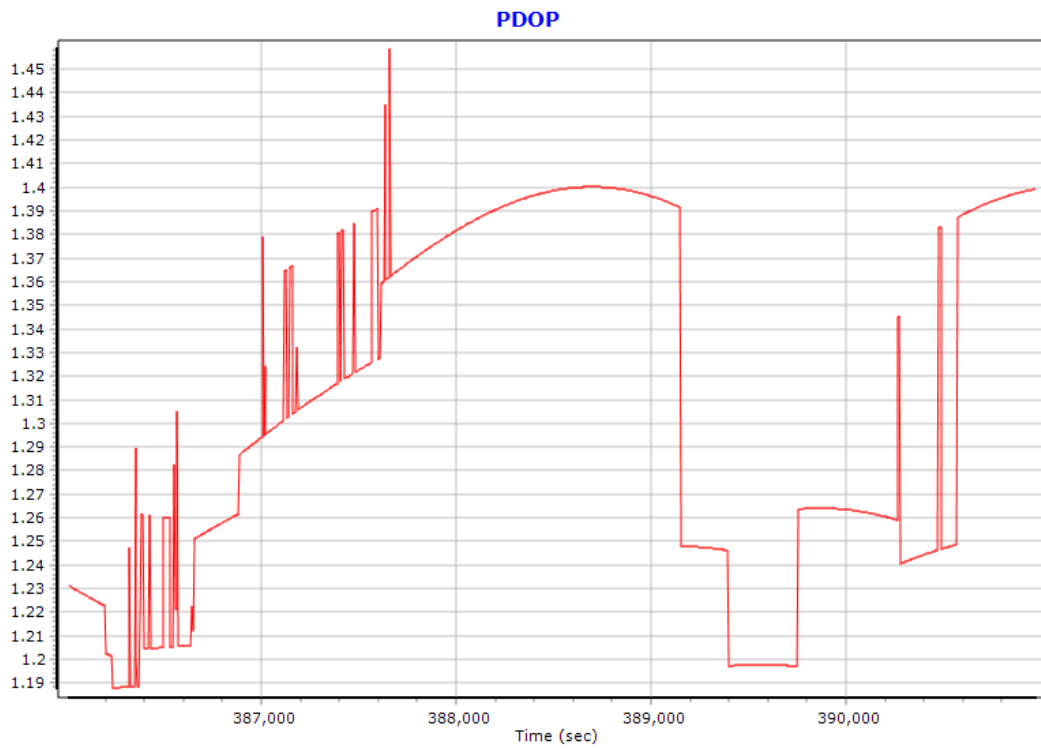
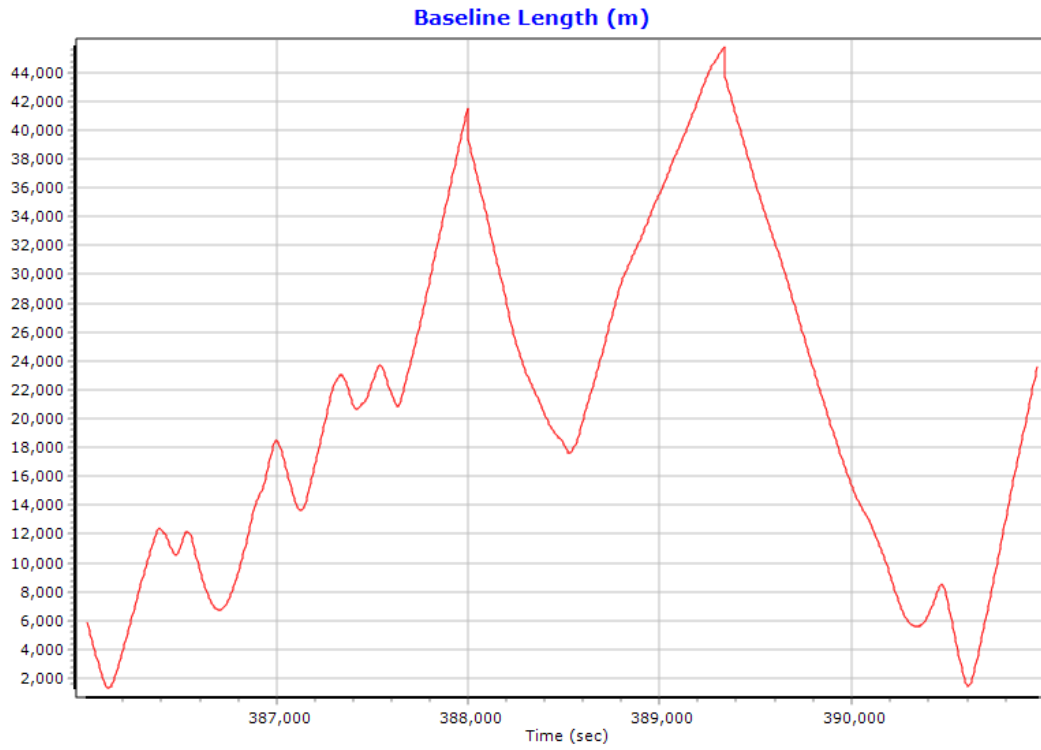
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

OK Cancel

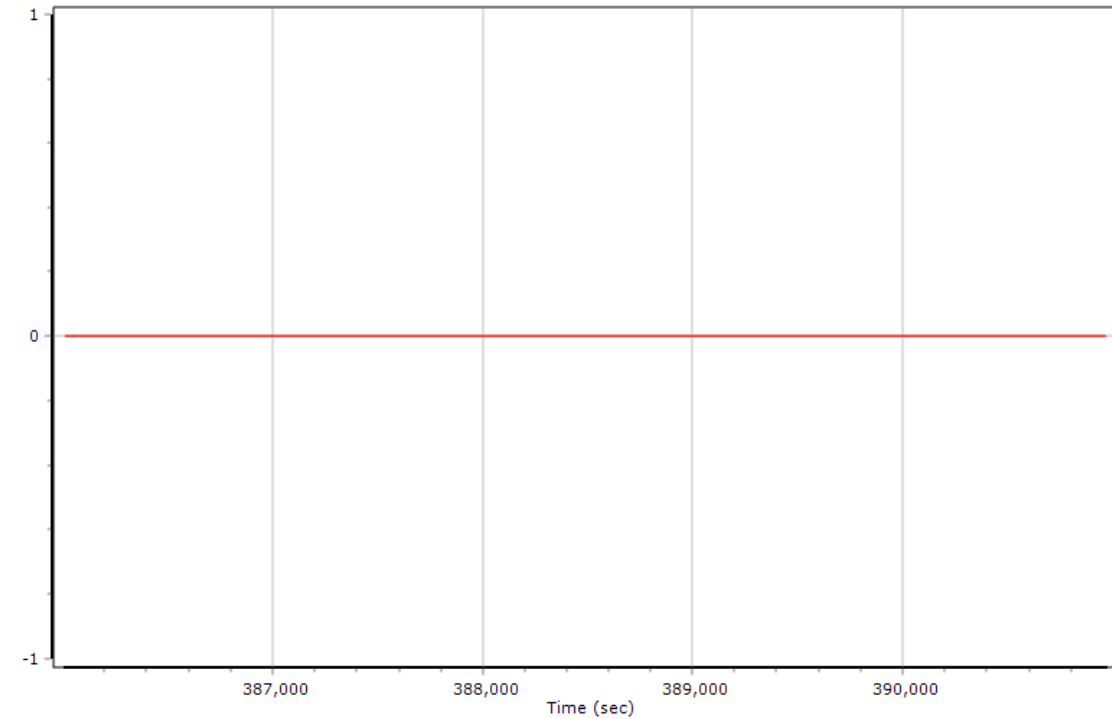






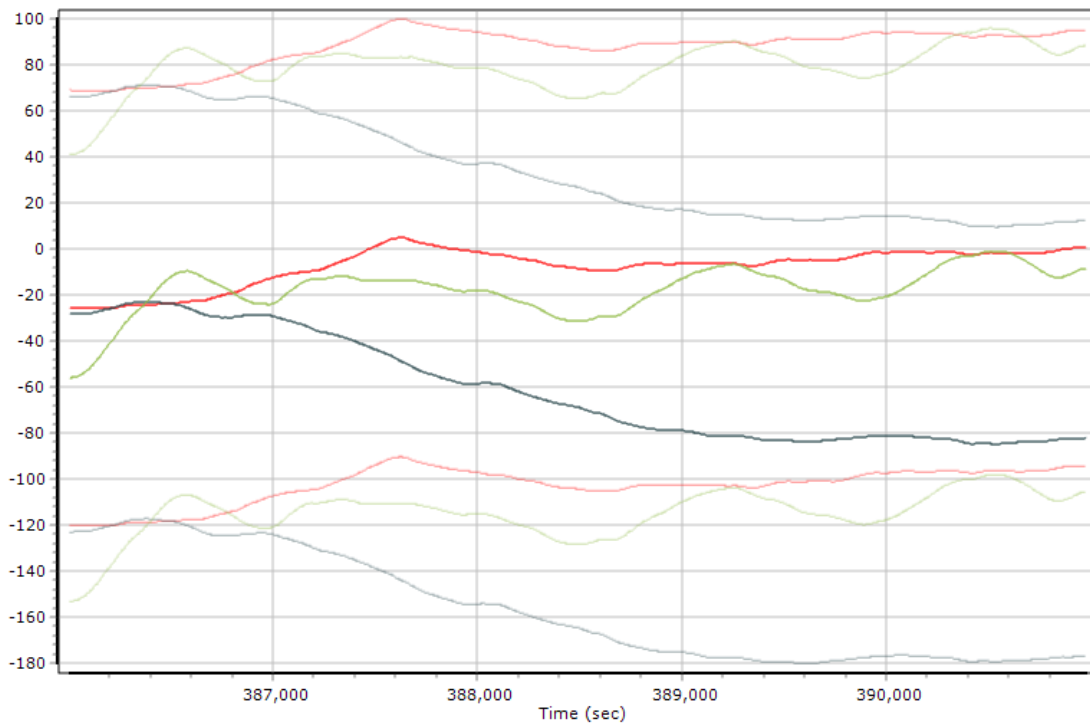


Processing mode

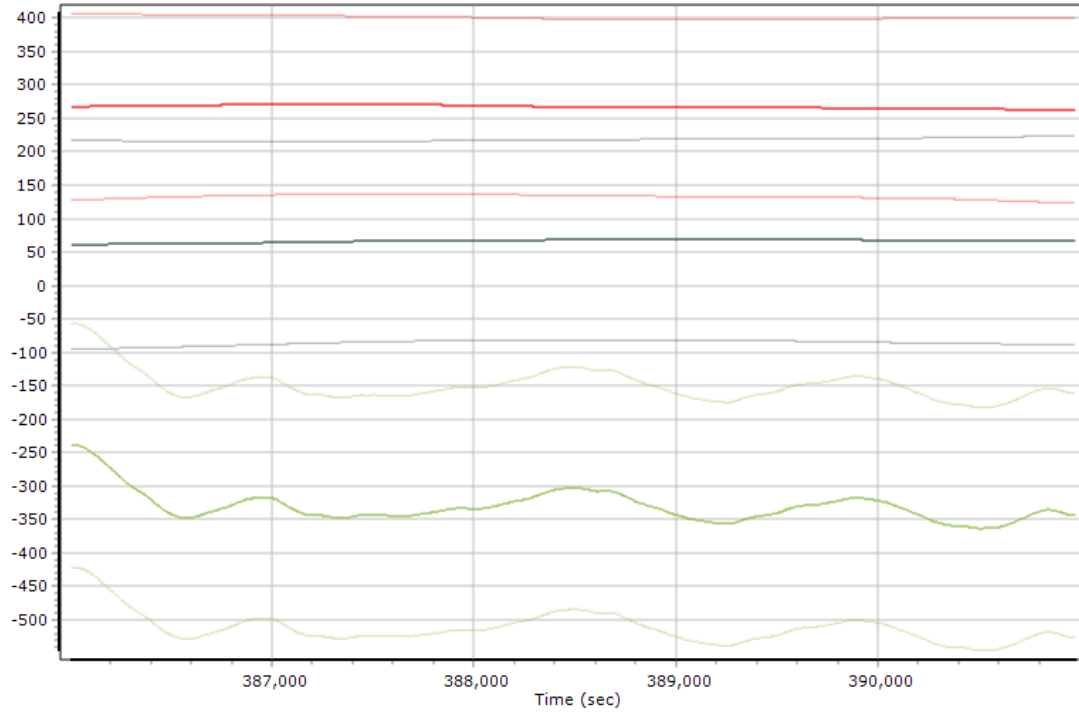


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

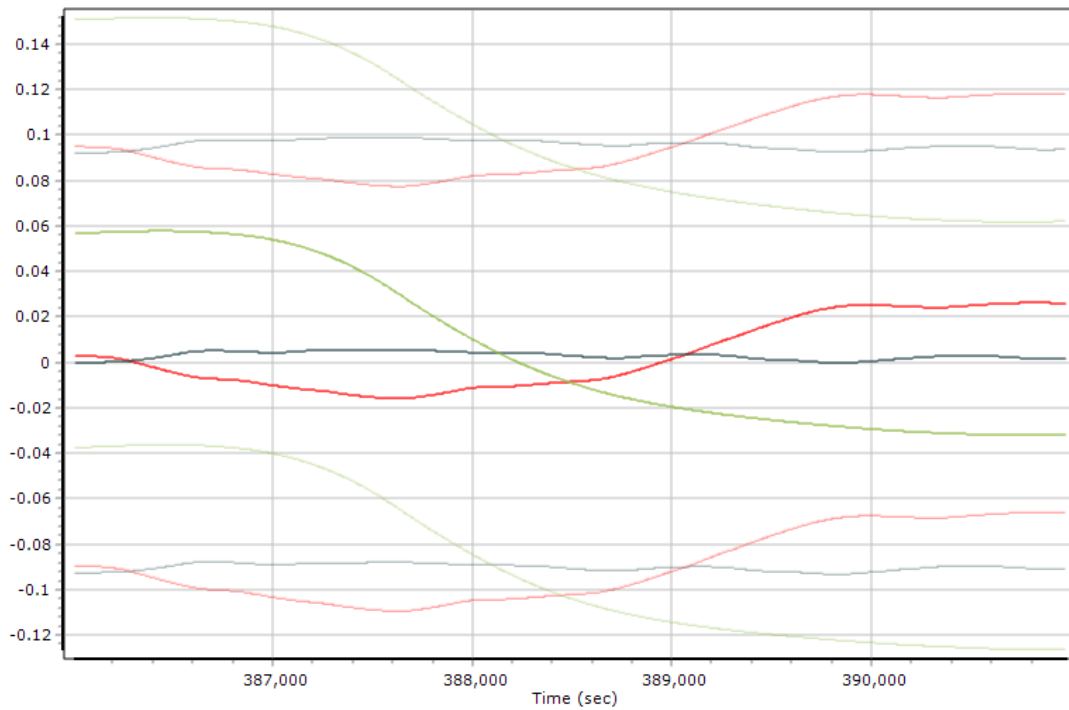
Sensor Errors



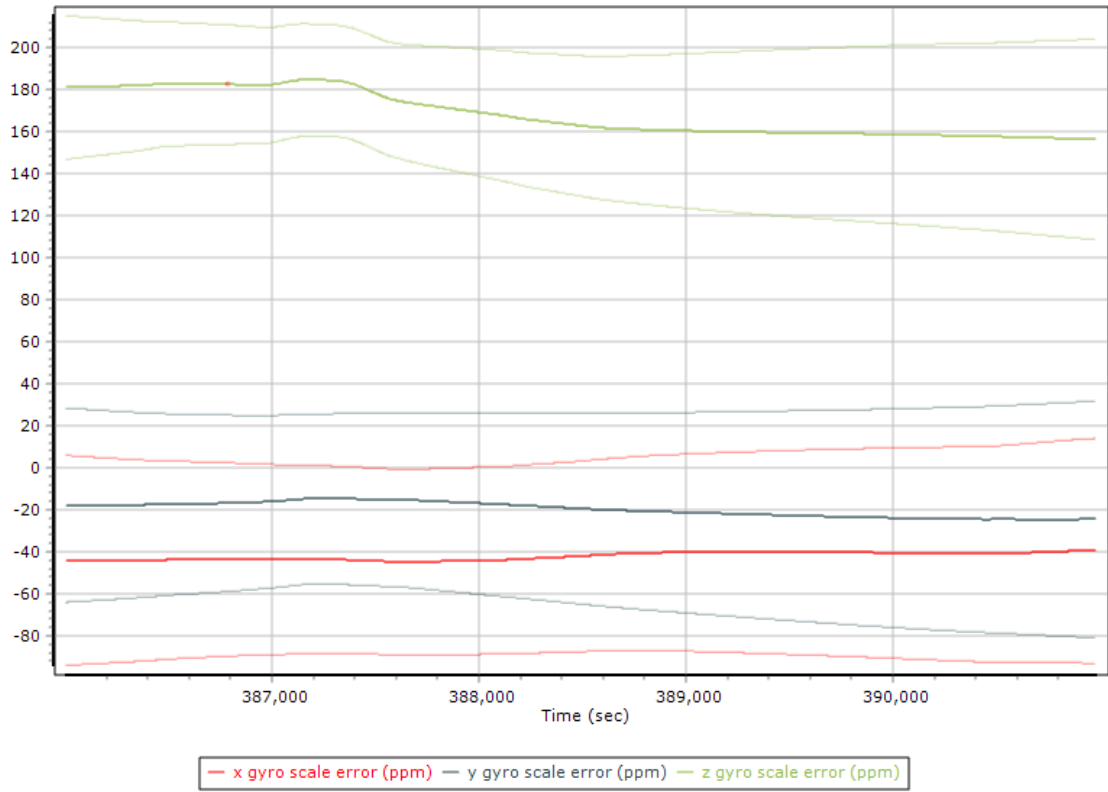
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)



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

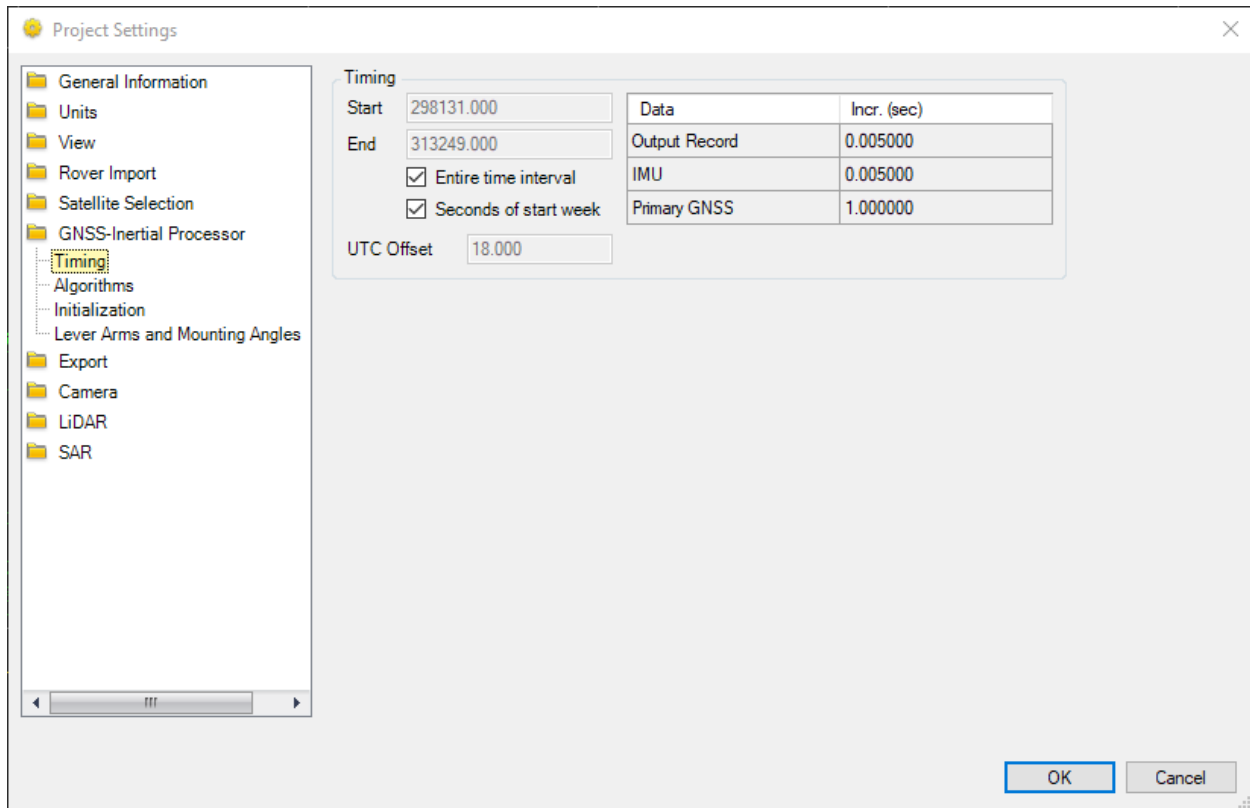
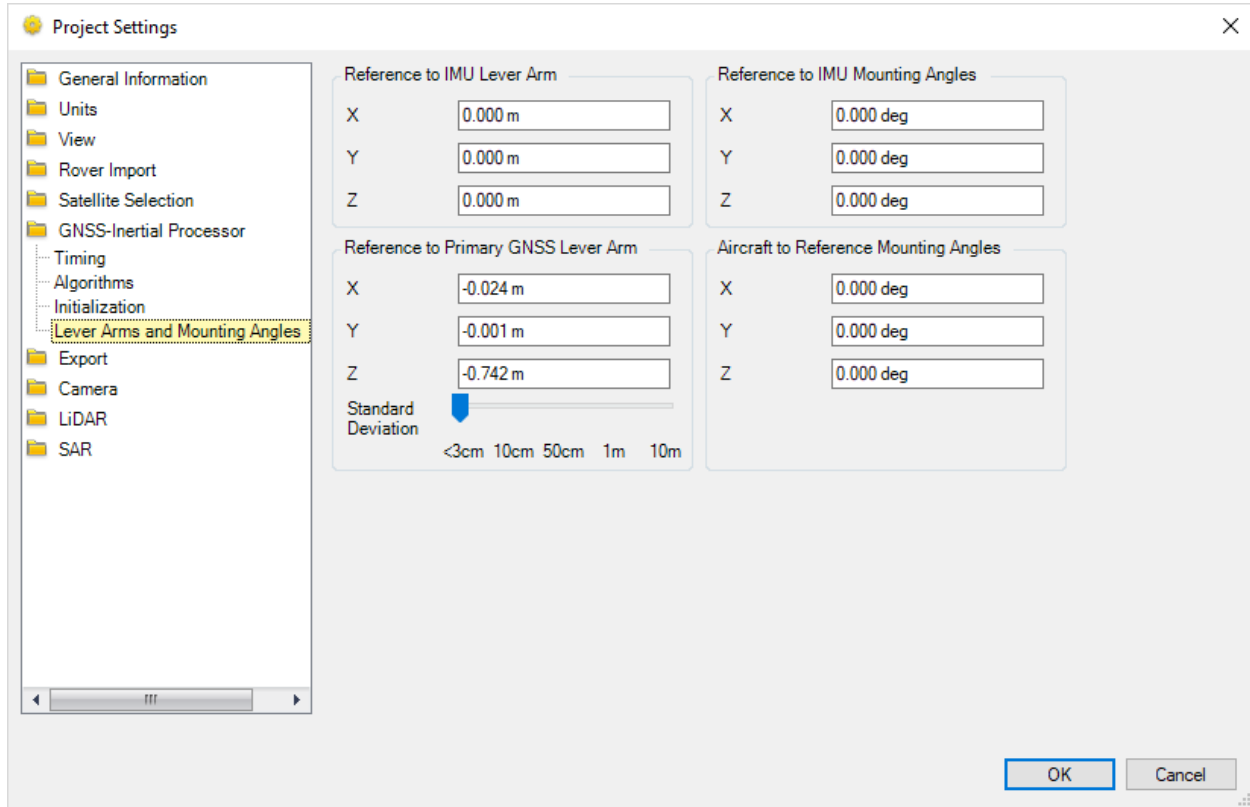


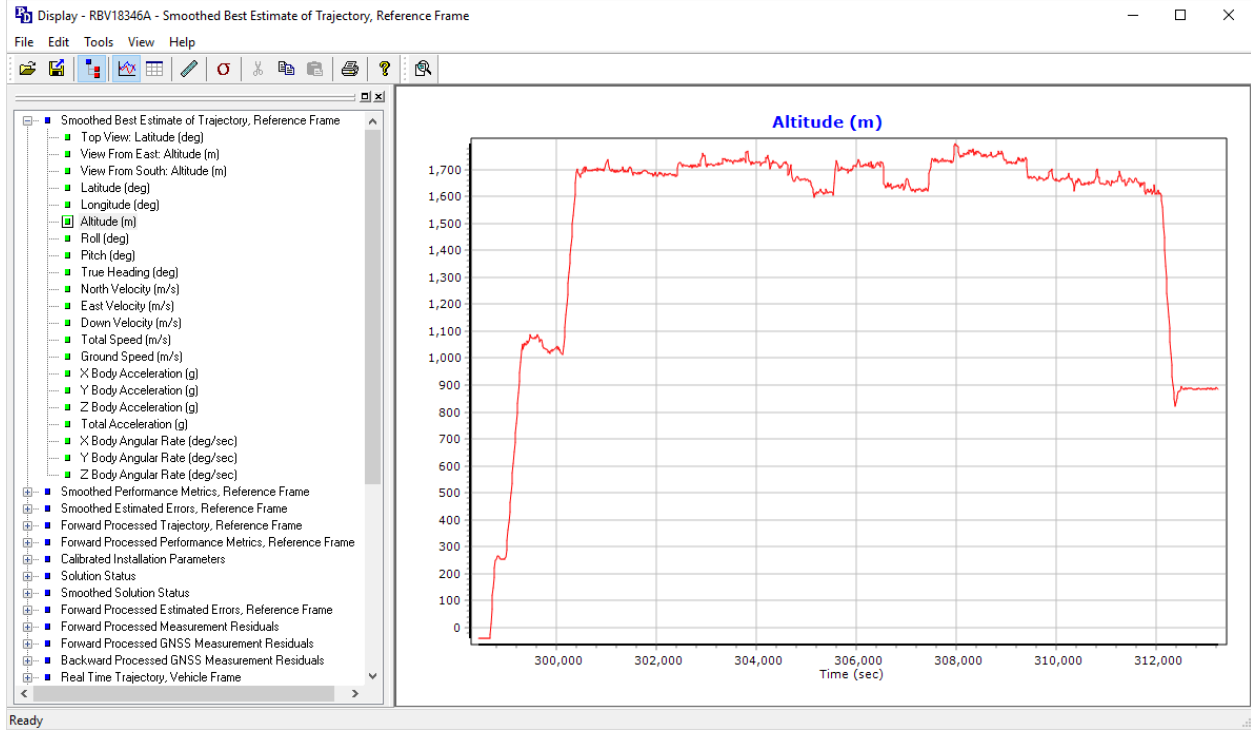
— x gyro bias (deg/hr) — y gyro bias (deg/hr) — z gyro bias (deg/hr)

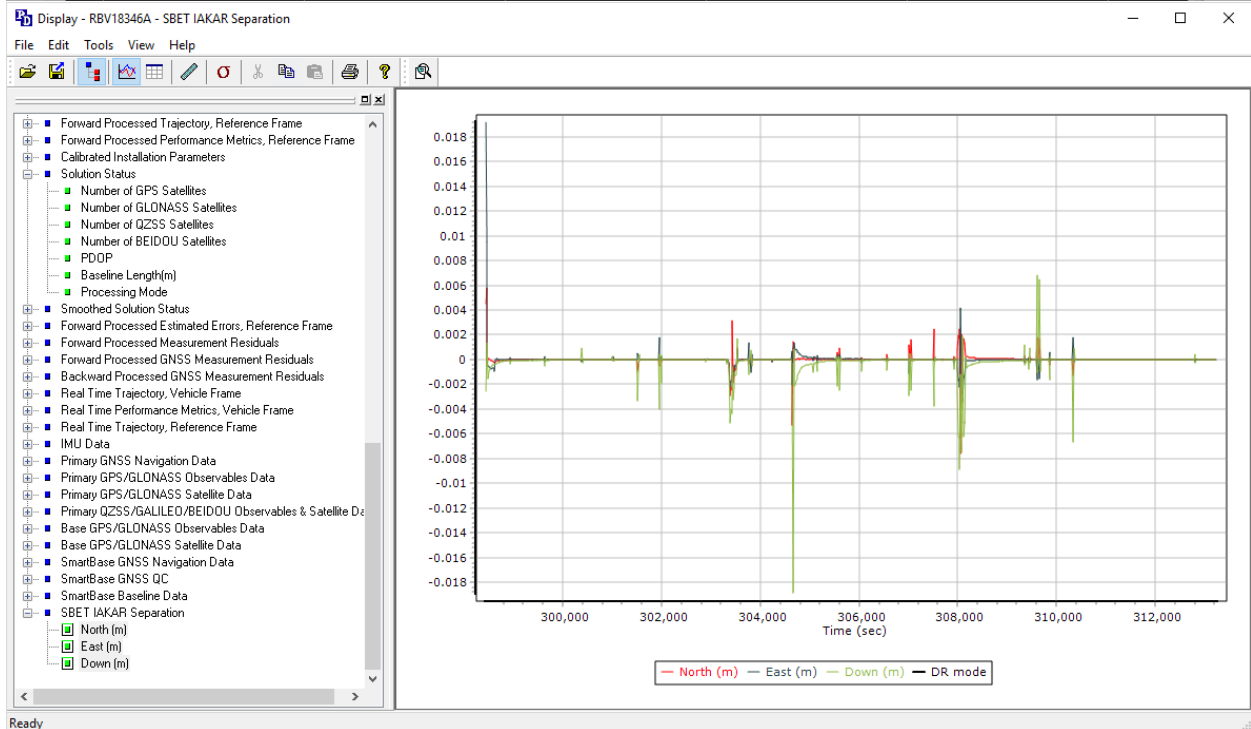
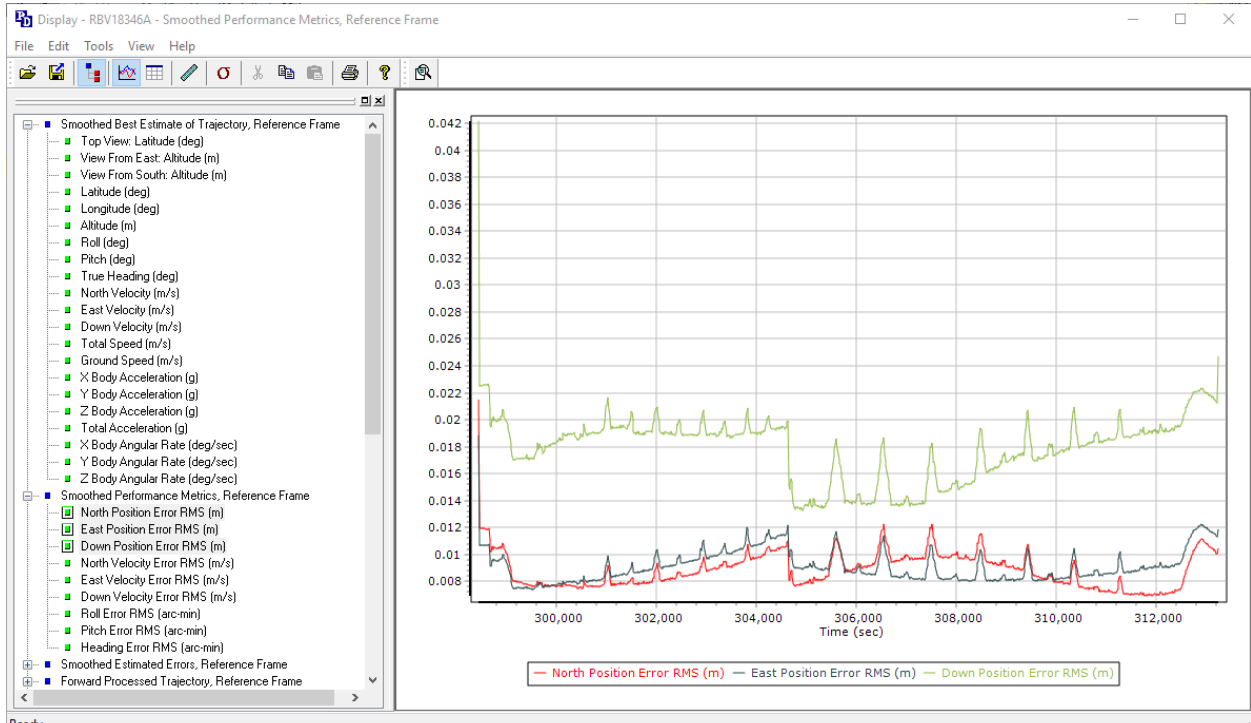


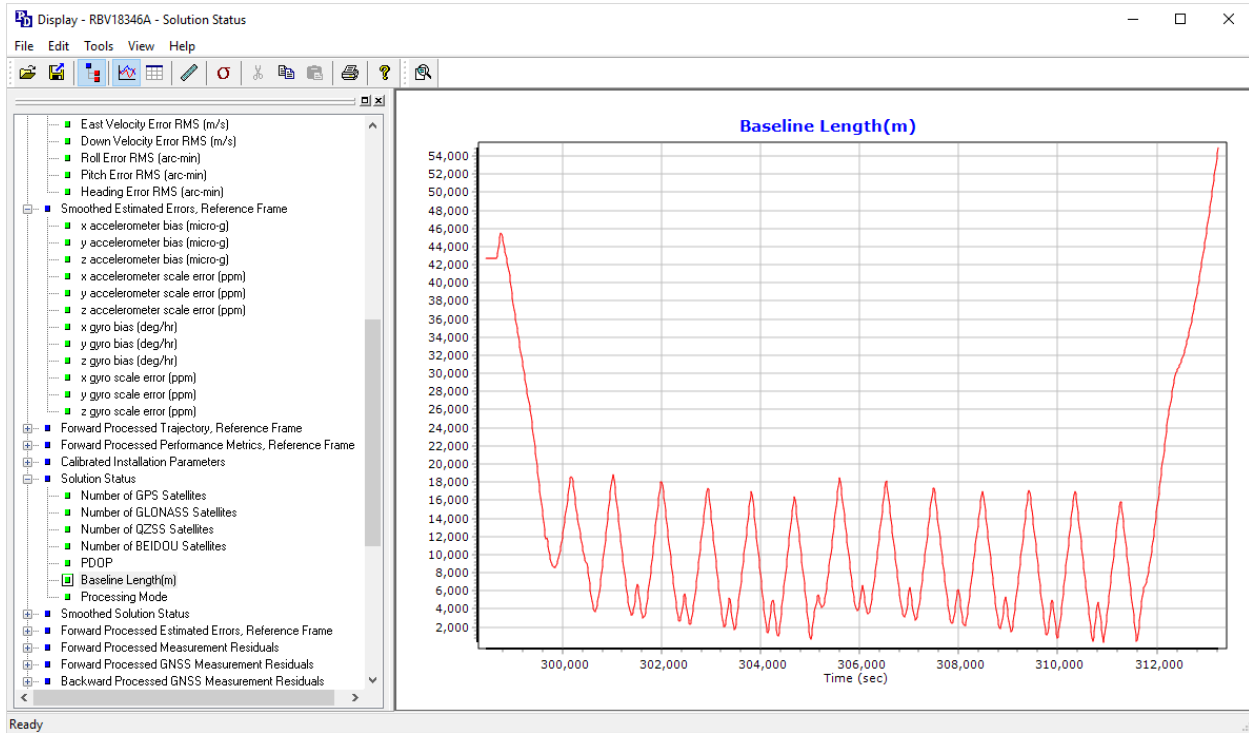
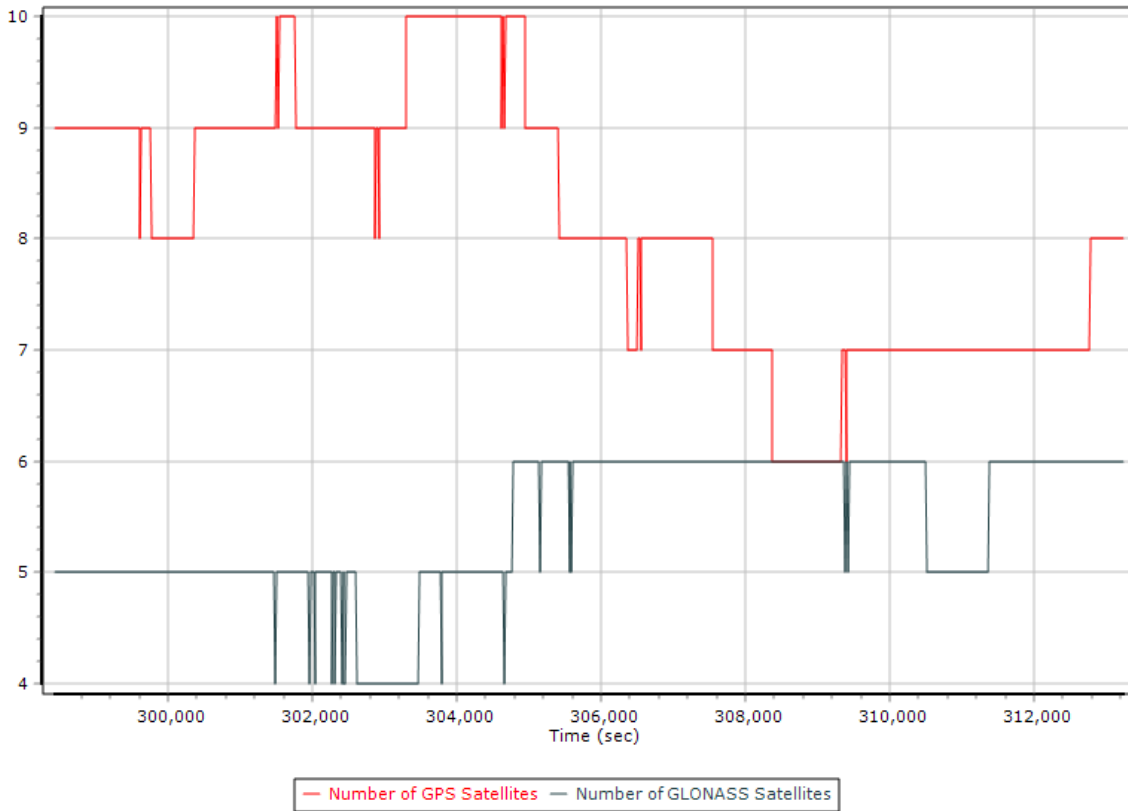
RBV18346A

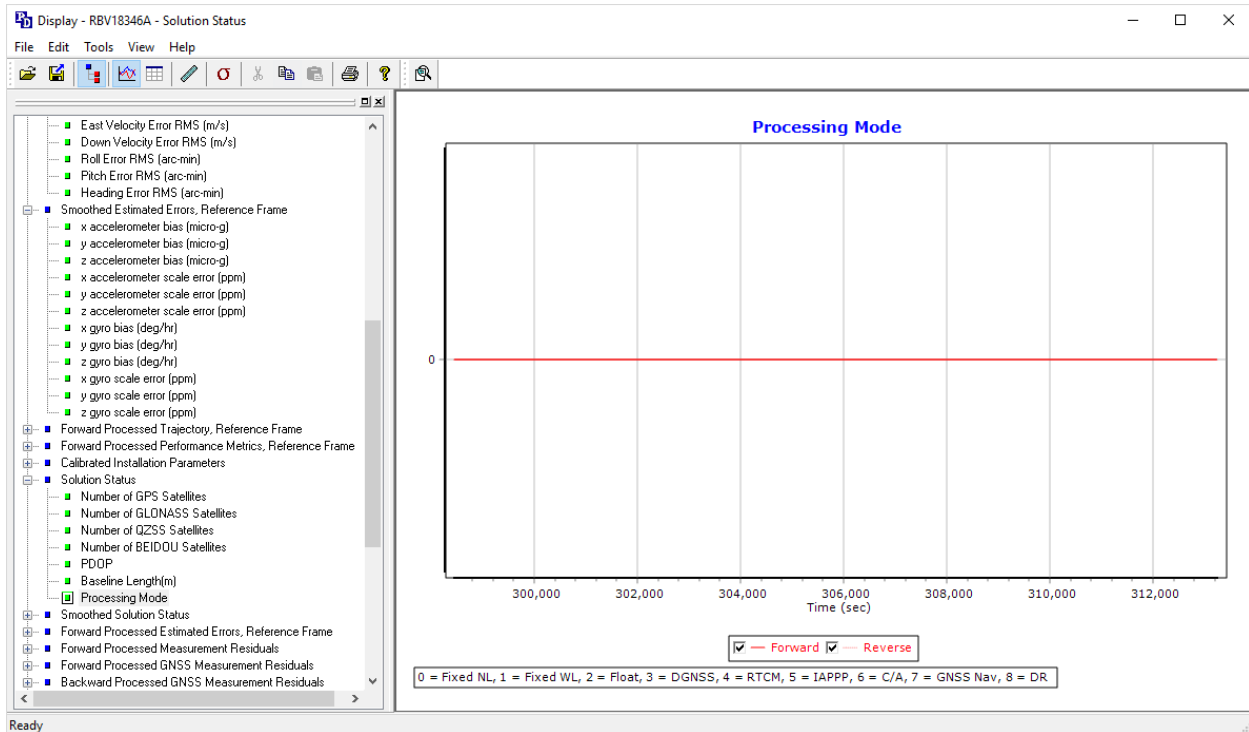
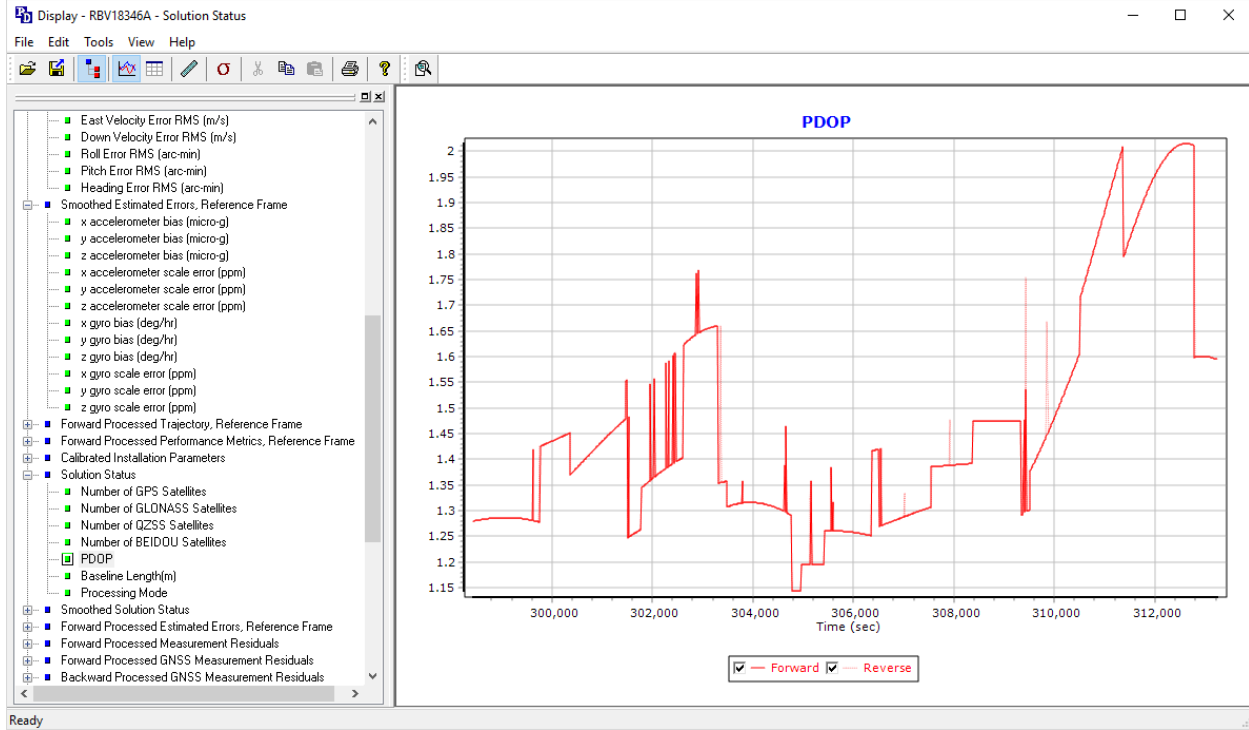
The screenshot shows the RBV18346A - POSpac MMS software interface. On the left is a Project Explorer with a tree view containing folders for 'RBV18346A', 'POS', 'Camera', 'LIDAR', 'SAR', 'Base Stations', and 'Imported Files'. The main window displays a 3D visualization of a network of points and connections, with labels for 'Start', 'PRM1', 'PRN4', 'PRN5', 'PRN6', 'PRN7', 'PRN8', 'PRN9', 'PRN10', 'PRN11', 'PRN12', 'PRN13', 'PRN14', 'PRN15', 'PRN16', 'PRN17', 'PRN18', 'PRN19', 'PRN20', 'PRN21', 'PRN22', 'PRN23', 'PRN24', 'PRN25', 'PRN26', 'PRN27', 'PRN28', 'PRN29', 'PRN30', 'PRN31', 'PRN32', 'PRN33', 'PRN34', 'PRN35', 'PRN36', 'PRN37', 'PRN38', 'PRN39', 'PRN40', 'PRN41', 'PRN42', 'PRN43', 'PRN44', 'PRN45', 'PRN46', 'PRN47', 'PRN48', 'PRN49', 'PRN50', 'PRN51', 'PRN52', 'PRN53', 'PRN54', 'PRN55', 'PRN56', 'PRN57', 'PRN58', 'PRN59', 'PRN60', 'PRN61', 'PRN62', 'PRN63', 'PRN64', 'PRN65', 'PRN66', 'PRN67', 'PRN68', 'PRN69', 'PRN70', 'PRN71', 'PRN72', 'PRN73', 'PRN74', 'PRN75', 'PRN76', 'PRN77', 'PRN78', 'PRN79', 'PRN80', 'PRN81', 'PRN82', 'PRN83', 'PRN84', 'PRN85', 'PRN86', 'PRN87', 'PRN88', 'PRN89', 'PRN90', 'PRN91', 'PRN92', 'PRN93', 'PRN94', 'PRN95', 'PRN96', 'PRN97', 'PRN98', 'PRN99', 'PRN100'. On the right is the GNSSE-Inertial Processor settings panel, which includes a 'Settings' section with fields for Mission (RBV18346A), GNSS Mode (IN-Fusion SmartBase), Stabilized Mount (None), and Base Station (ASB). Below this is a 'Status' section showing Termination Stat. as Normal and Position Accuracy as 0.01. A 'Message Log' section at the bottom right contains the following text: 'RTS Smoother (Aug 29 2018) Copyright (c) 2008-2018 Applanix Corporation. All rights reserved. Date: 12/18/18 Time: 13:05:13 Processed data path: F:\2018-1841-3641-Puerto_F... Processed data kernel: RBV18346A Nominal I/N time increment: 0.0050 Output SBET time increment: 0.0050 Computing smoothed states: Processing started Writing SBET Termination status: Normal Execution time: 1:77:55 ITS smoother completed'. At the bottom of the interface, there are 'Run' and 'Close' buttons.



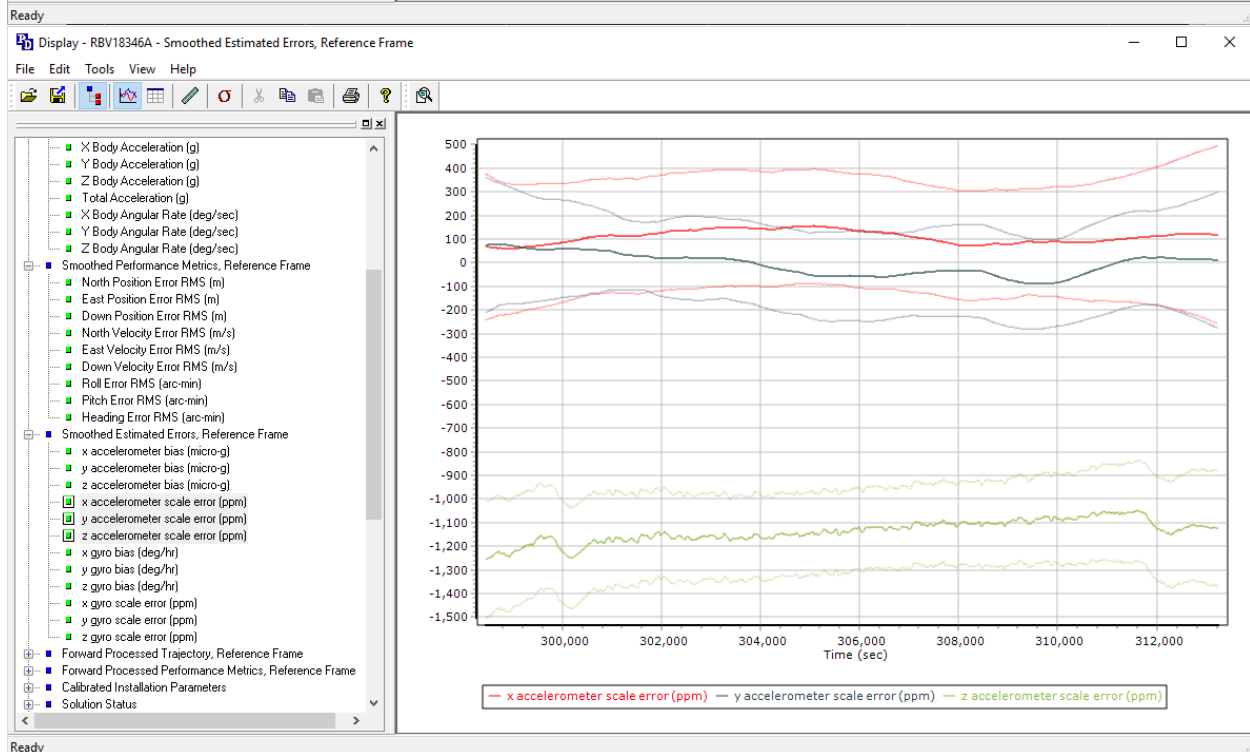
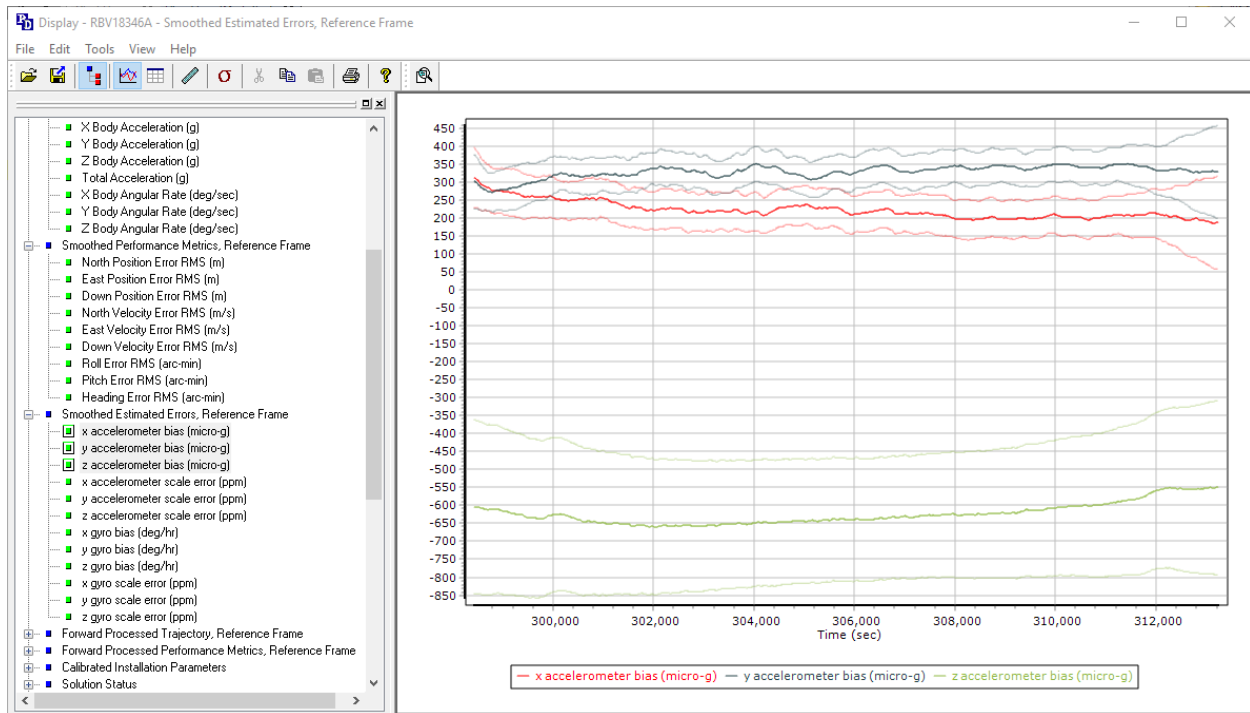


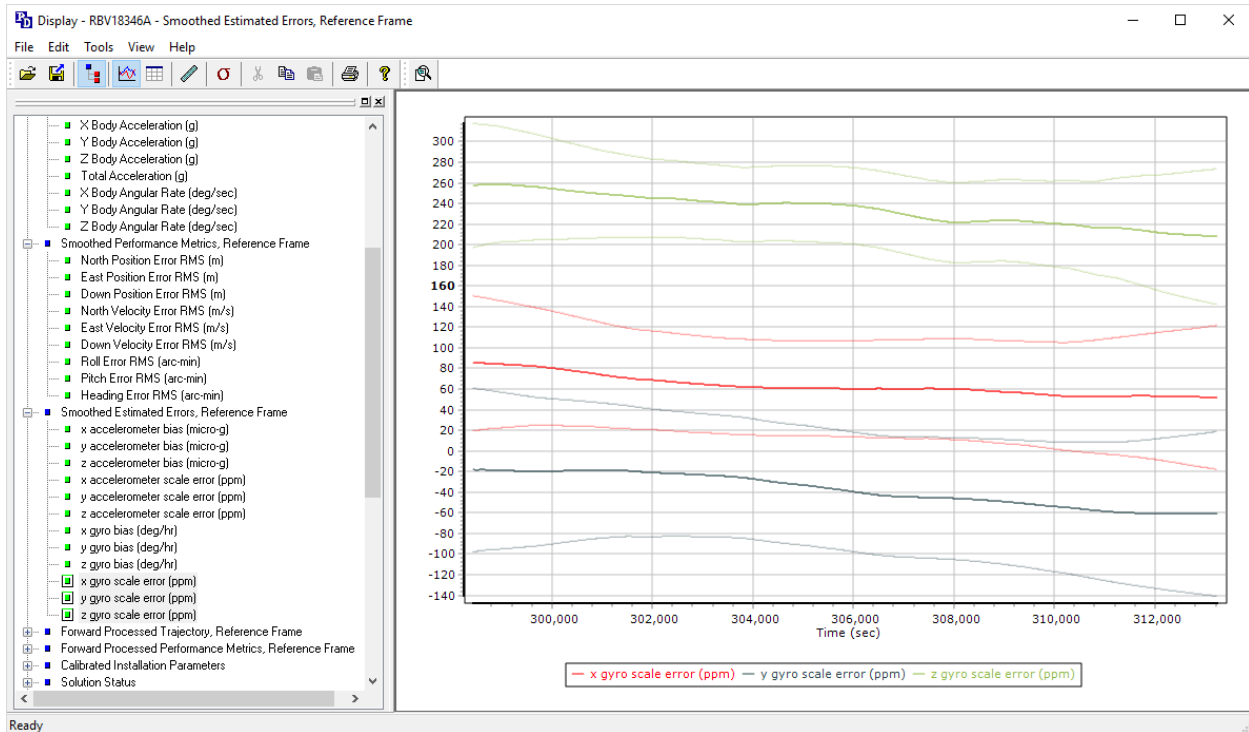
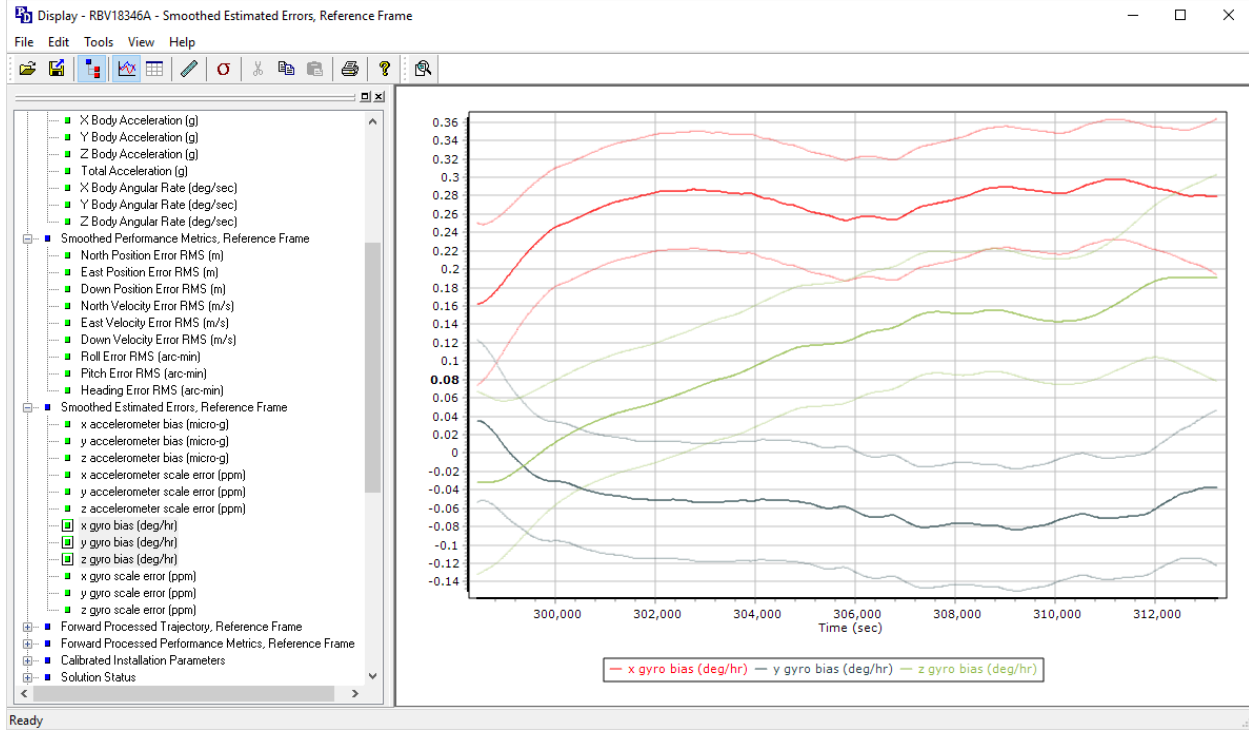




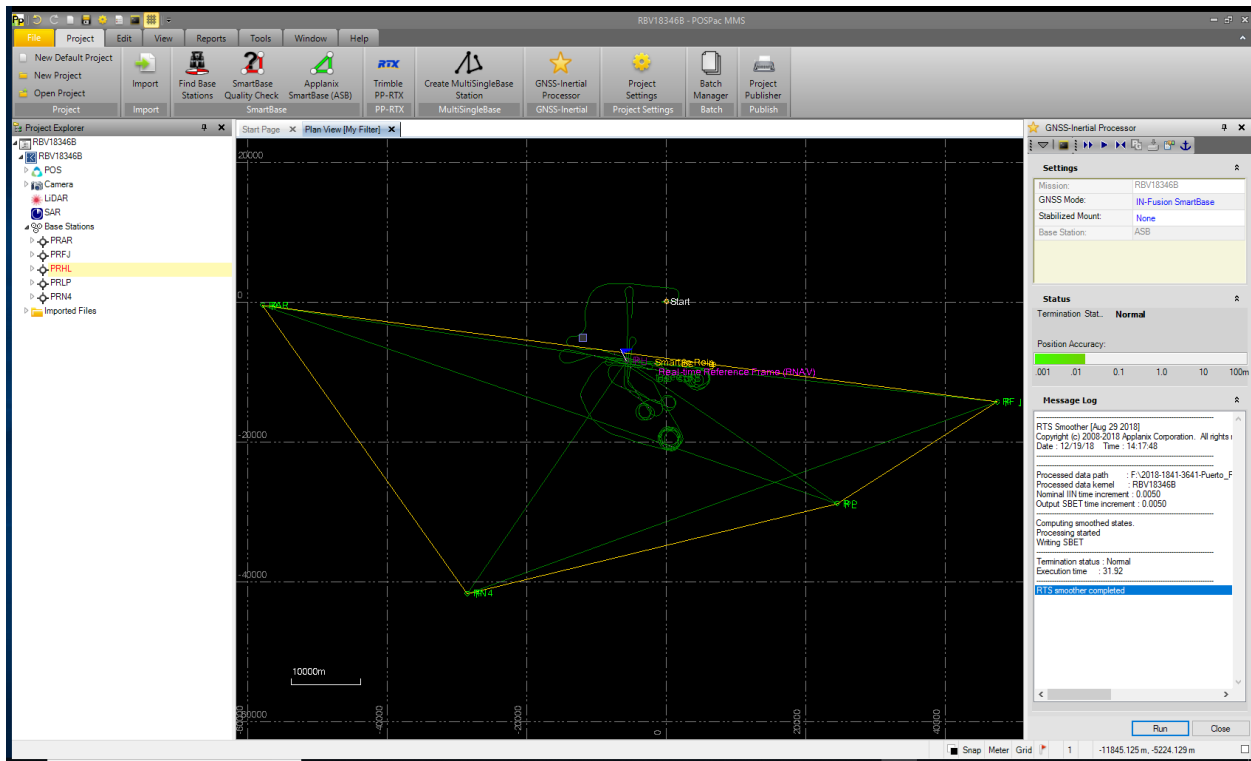


Sensor Errors





RBV18346B



The Project Settings dialog box is shown, with the 'Lever Arms and Mounting Angles' section selected in the left-hand menu. The settings are as follows:

Reference to IMU Lever Arm	Reference to IMU Mounting Angles
X: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 m	Z: 0.000 deg

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

Buttons: OK, Cancel

Project Settings

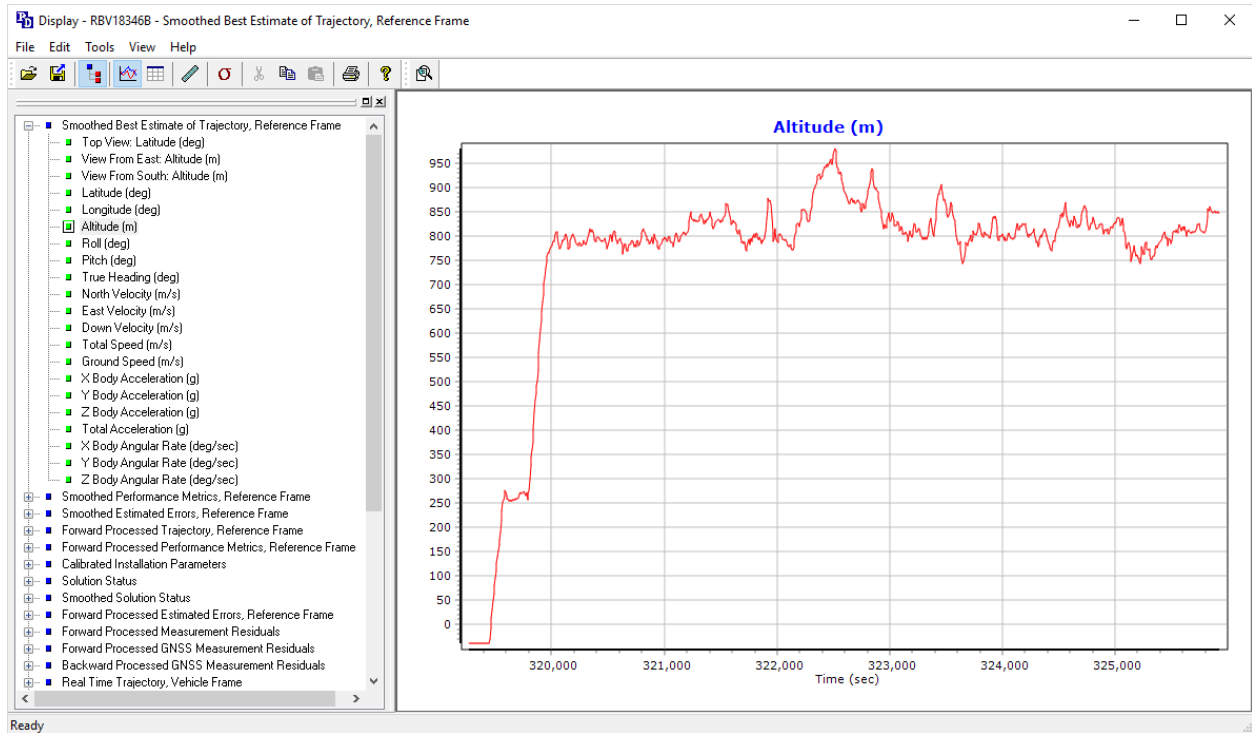
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
 Timing
 Algorithms
 Initialization
 Lever Arms and Mounting Angles
Export
Camera
LiDAR
SAR

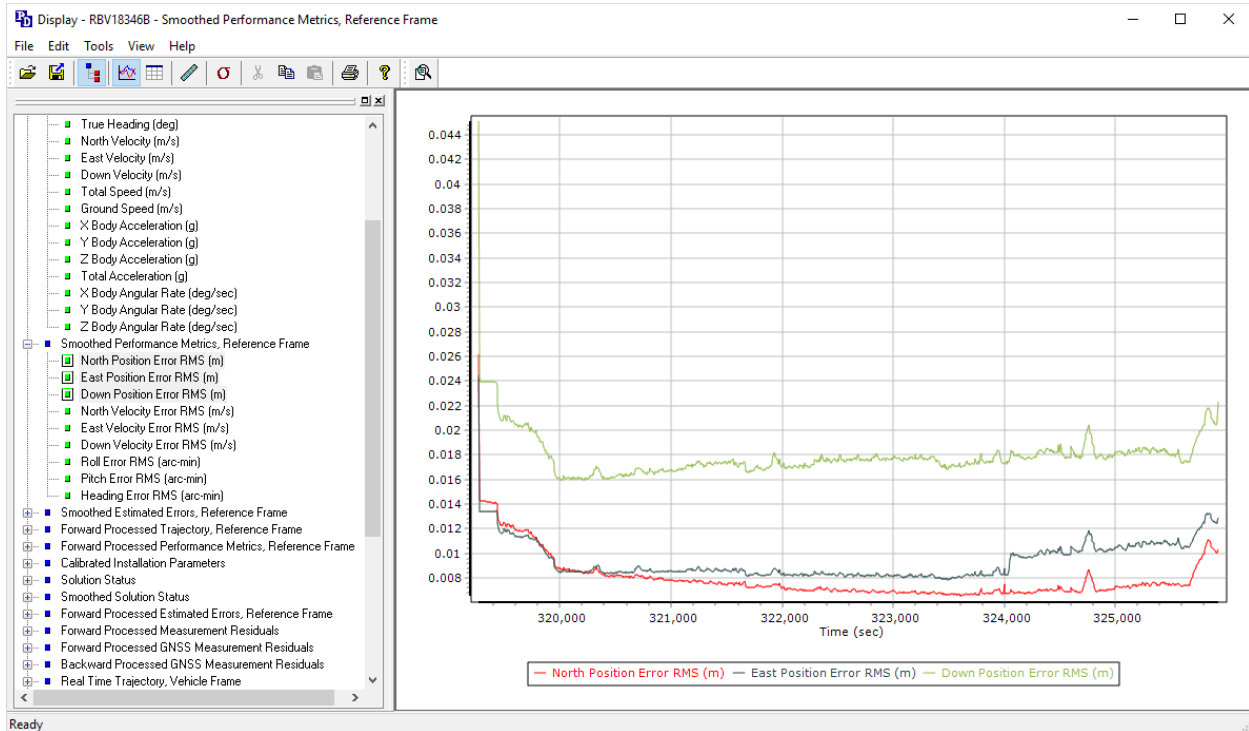
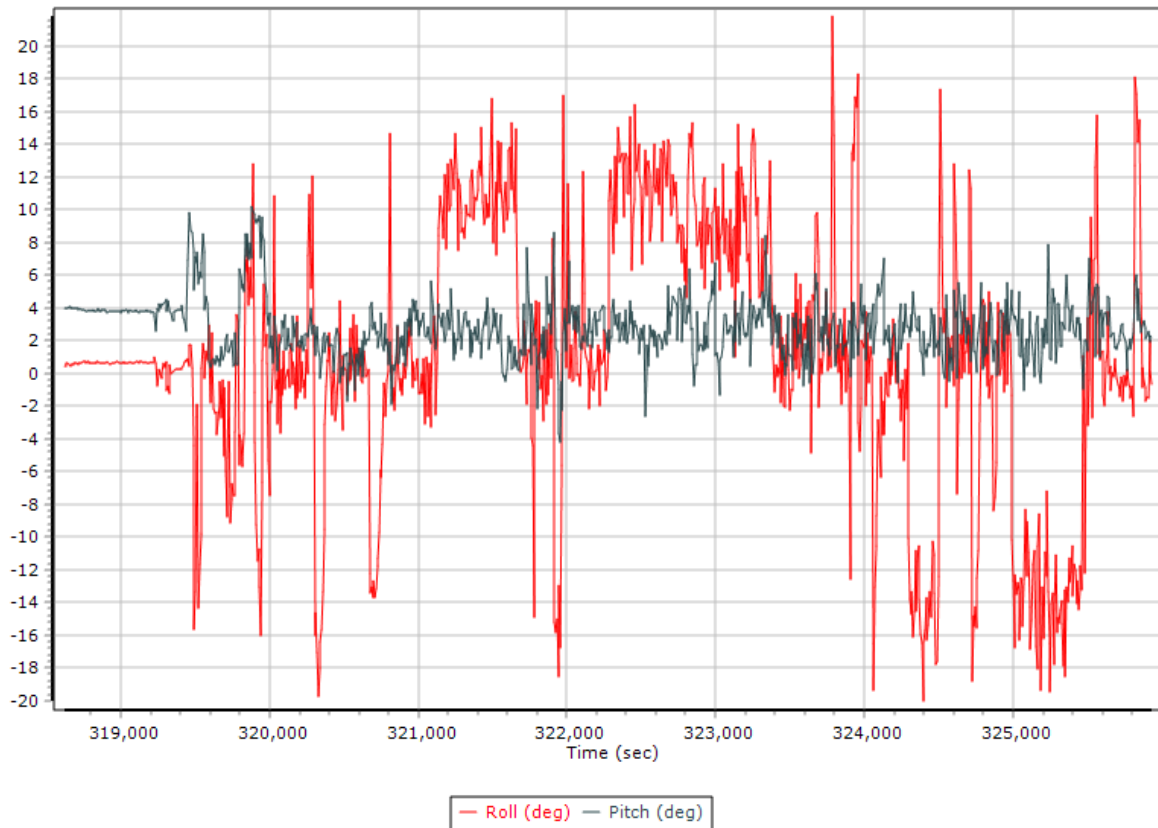
Timing

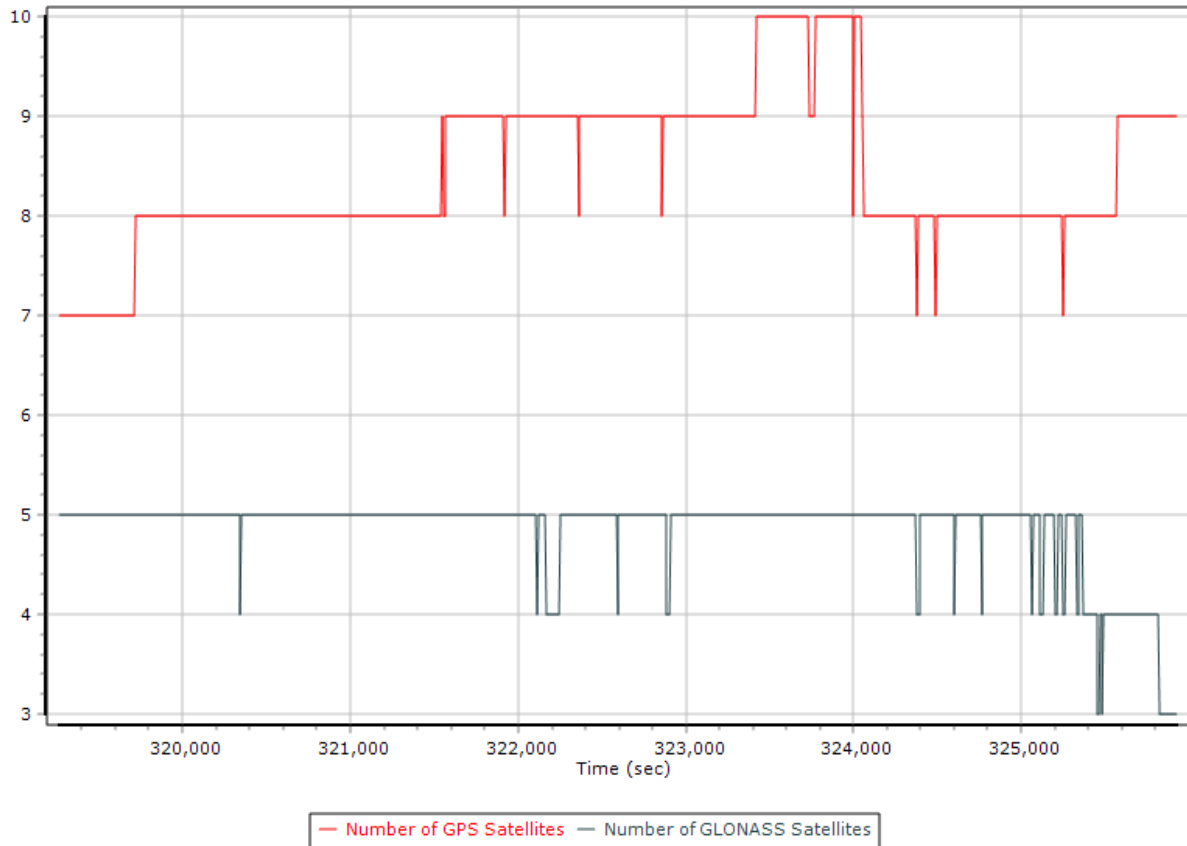
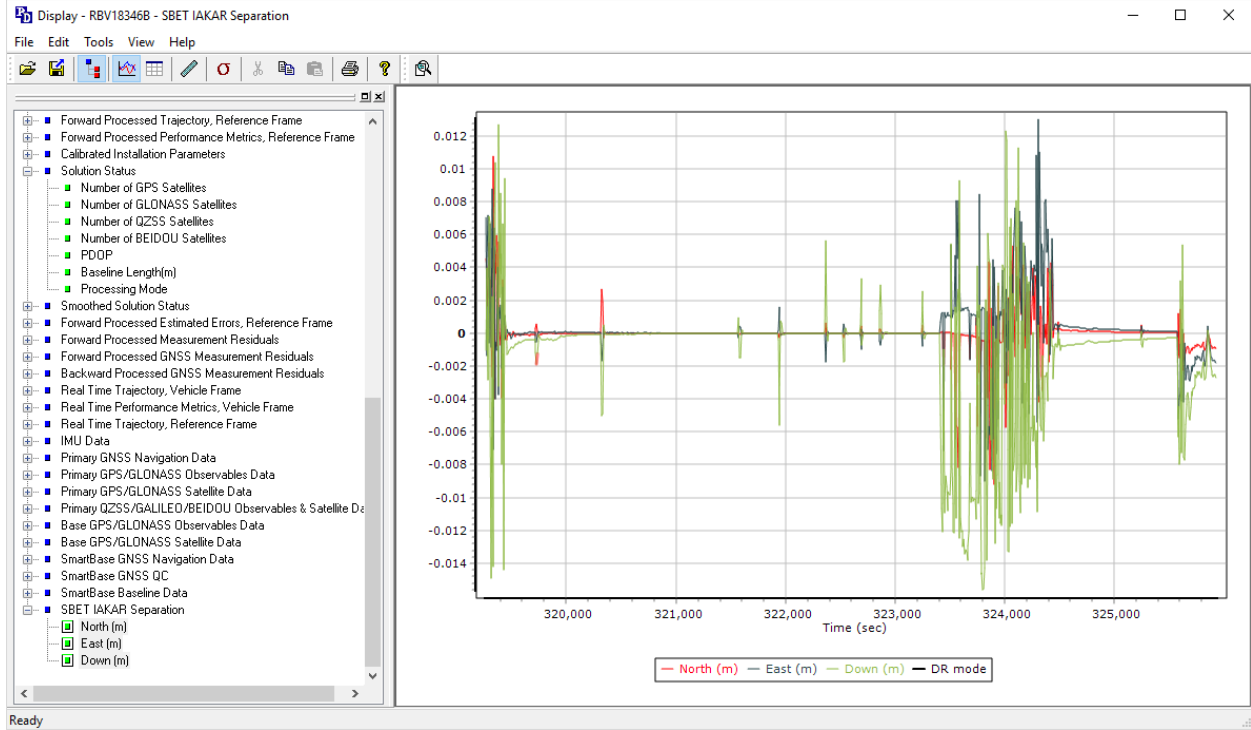
Start: 318624.021
End: 325930.000
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

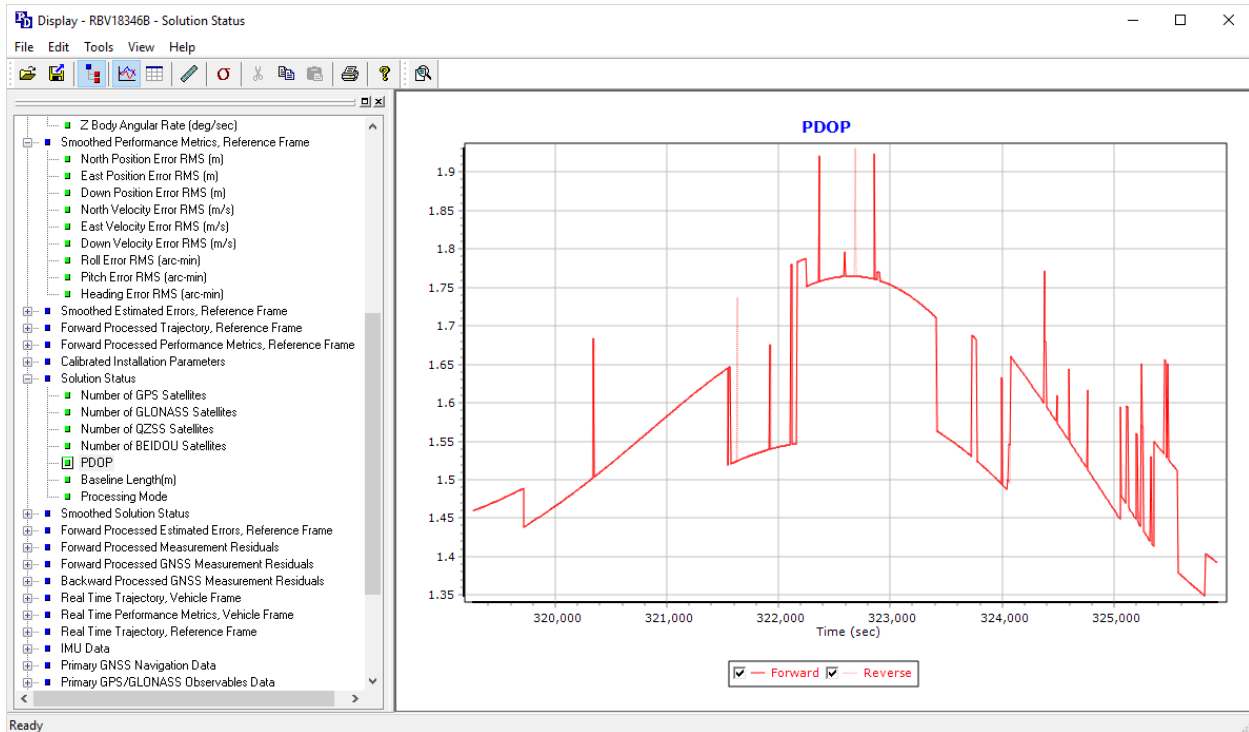
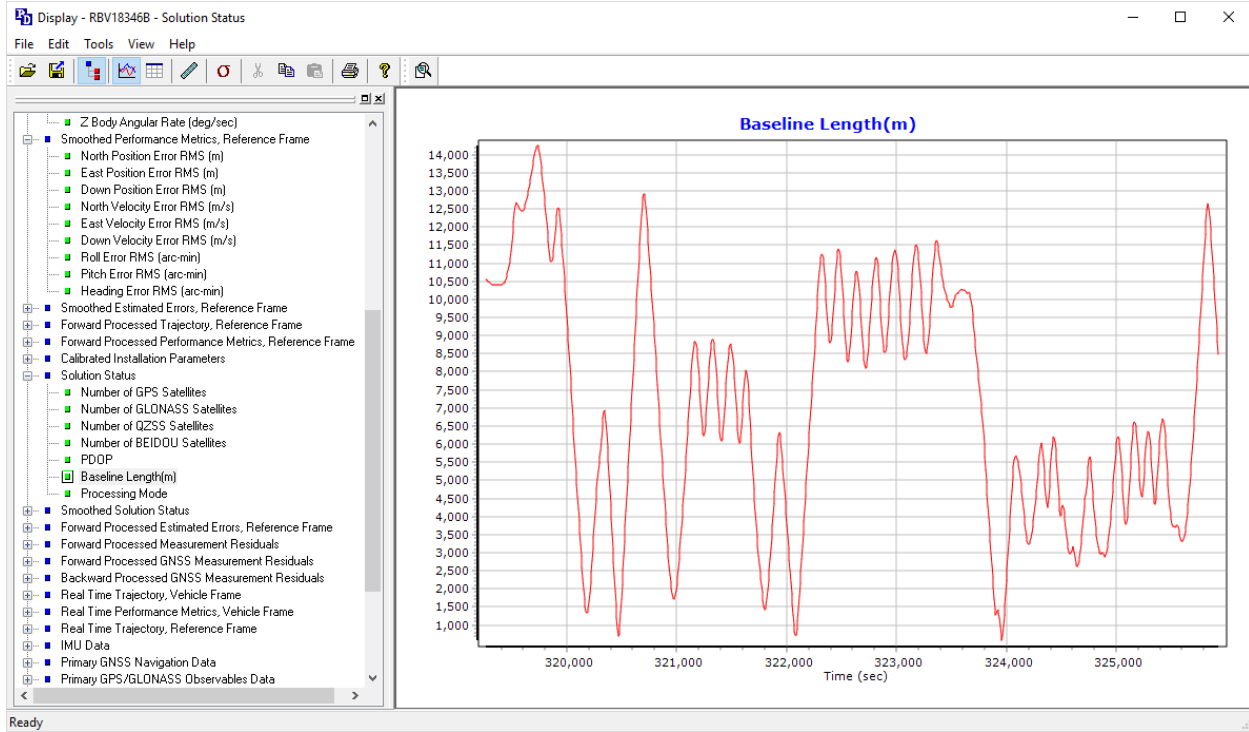
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

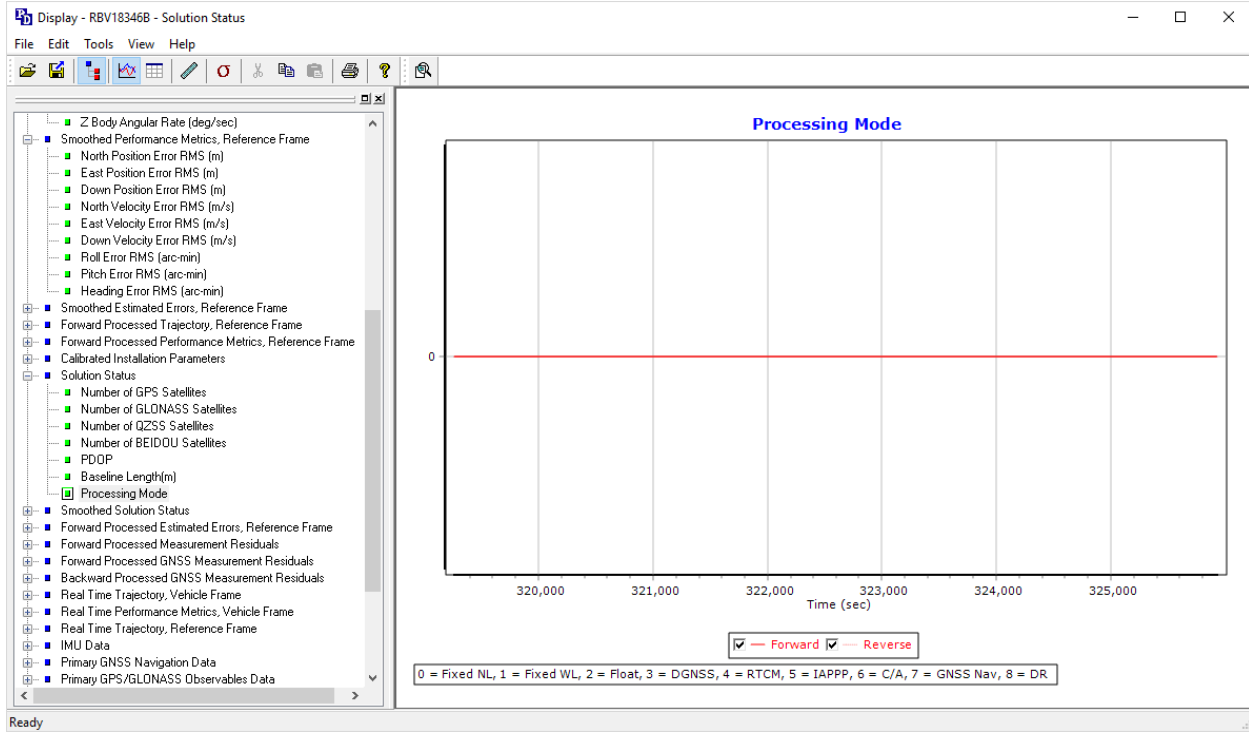
OK Cancel



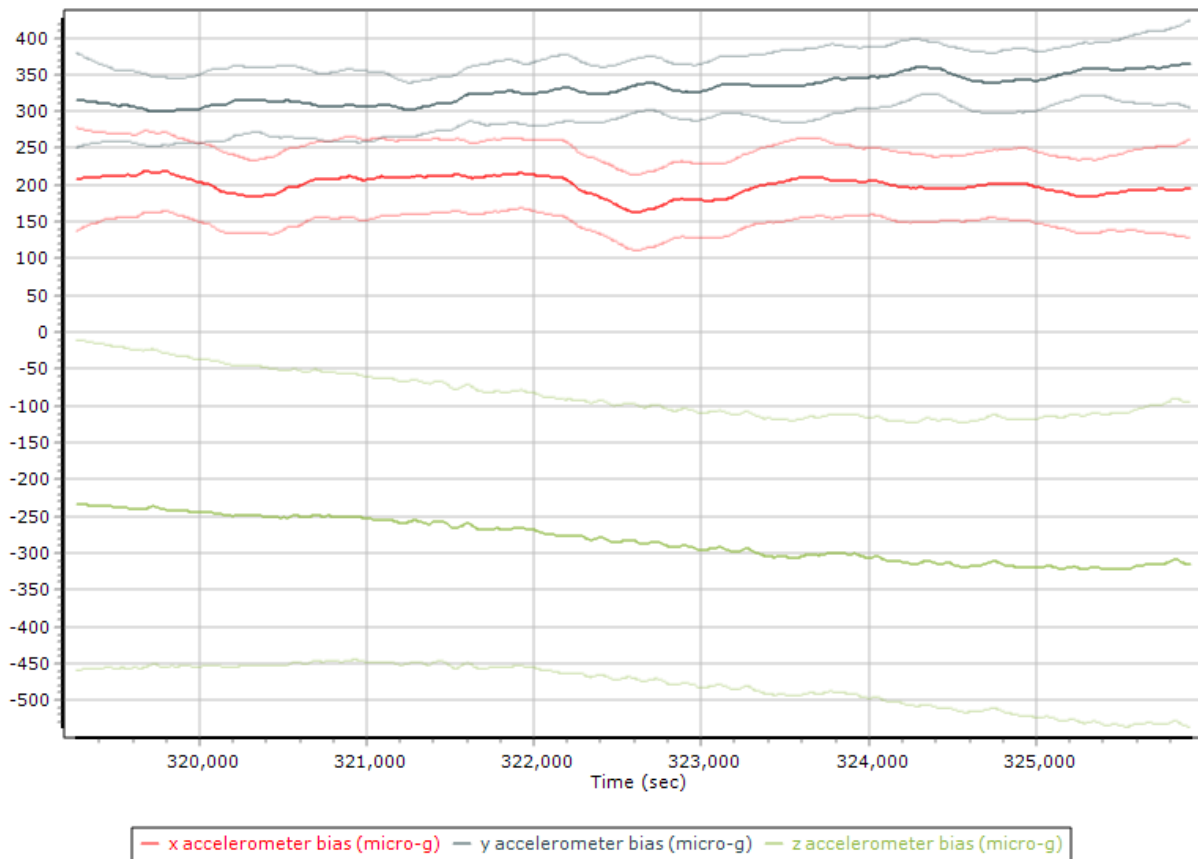


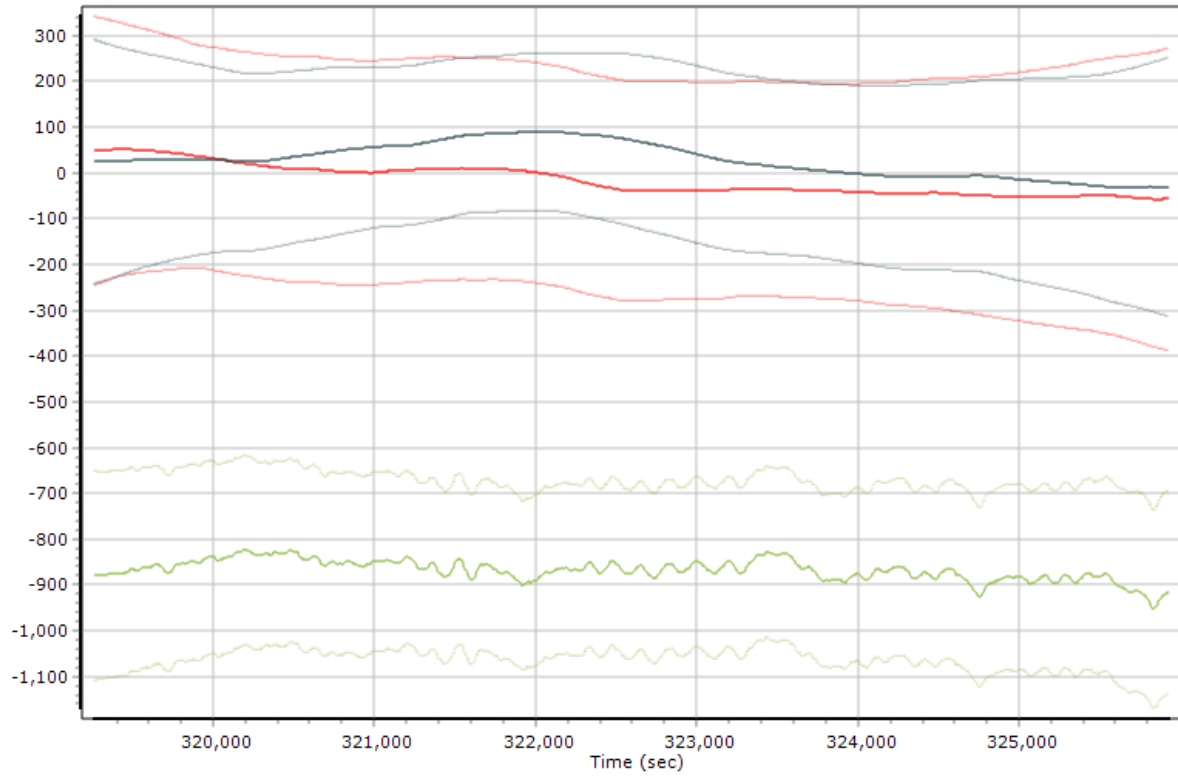




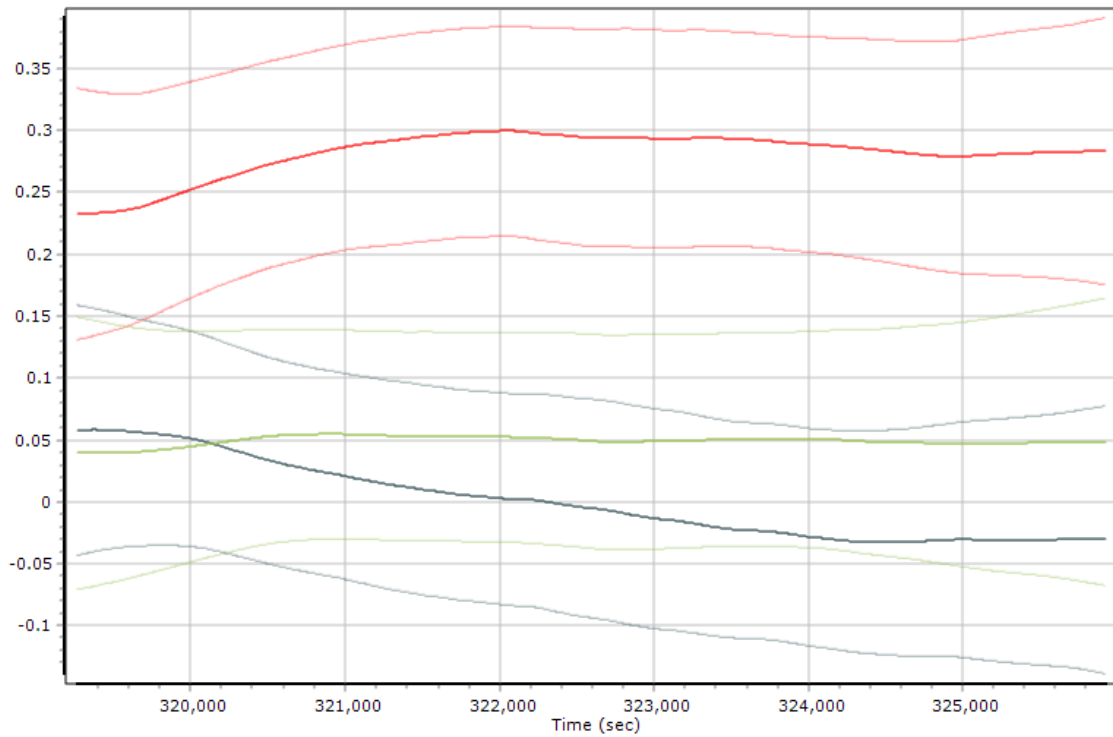


Sensor Errors

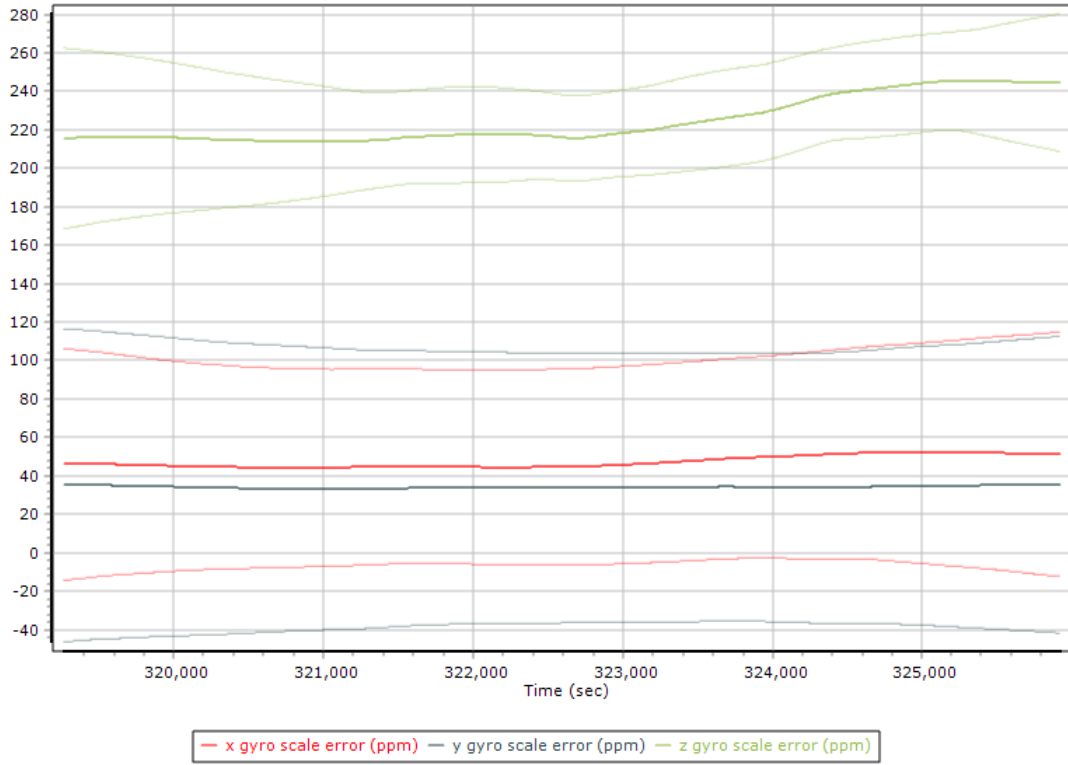




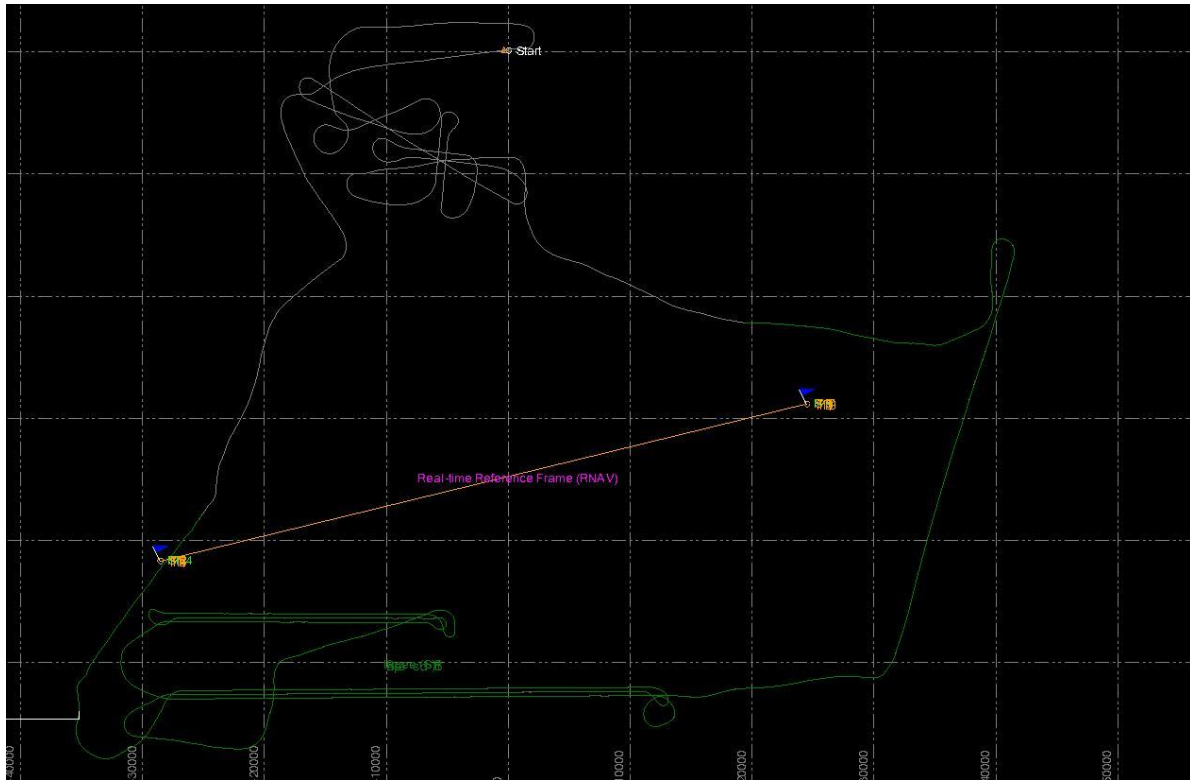
— x accelerometer scale error (ppm) — y accelerometer scale error (ppm) — z accelerometer scale error (ppm)




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

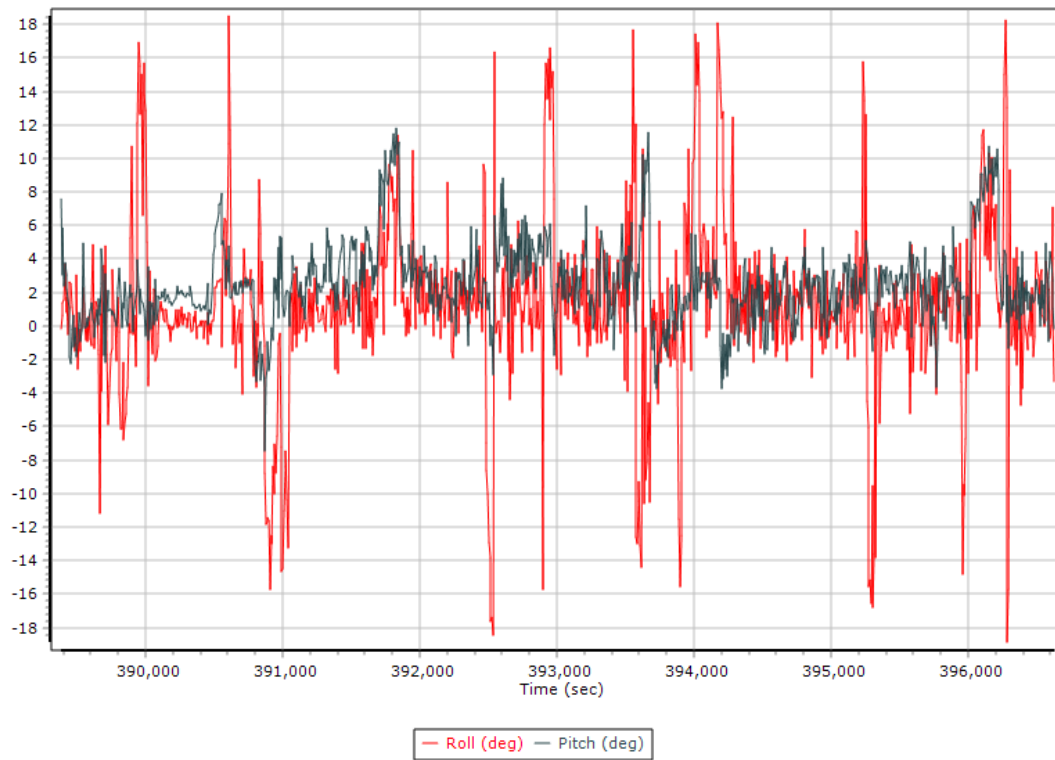
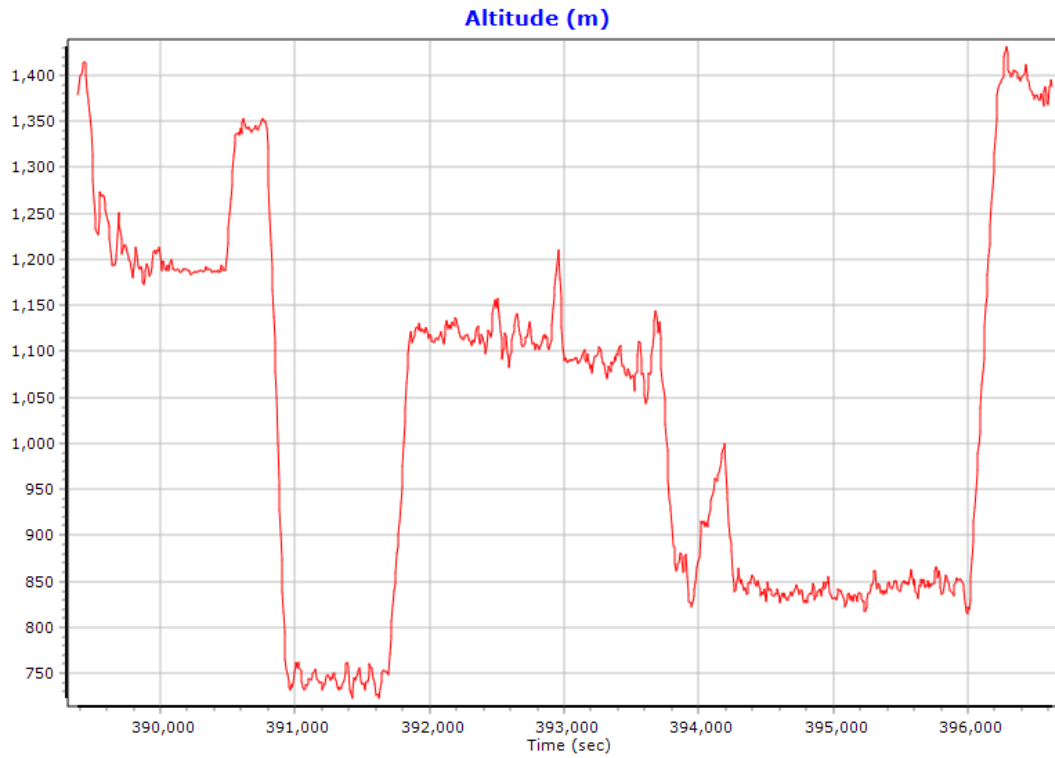


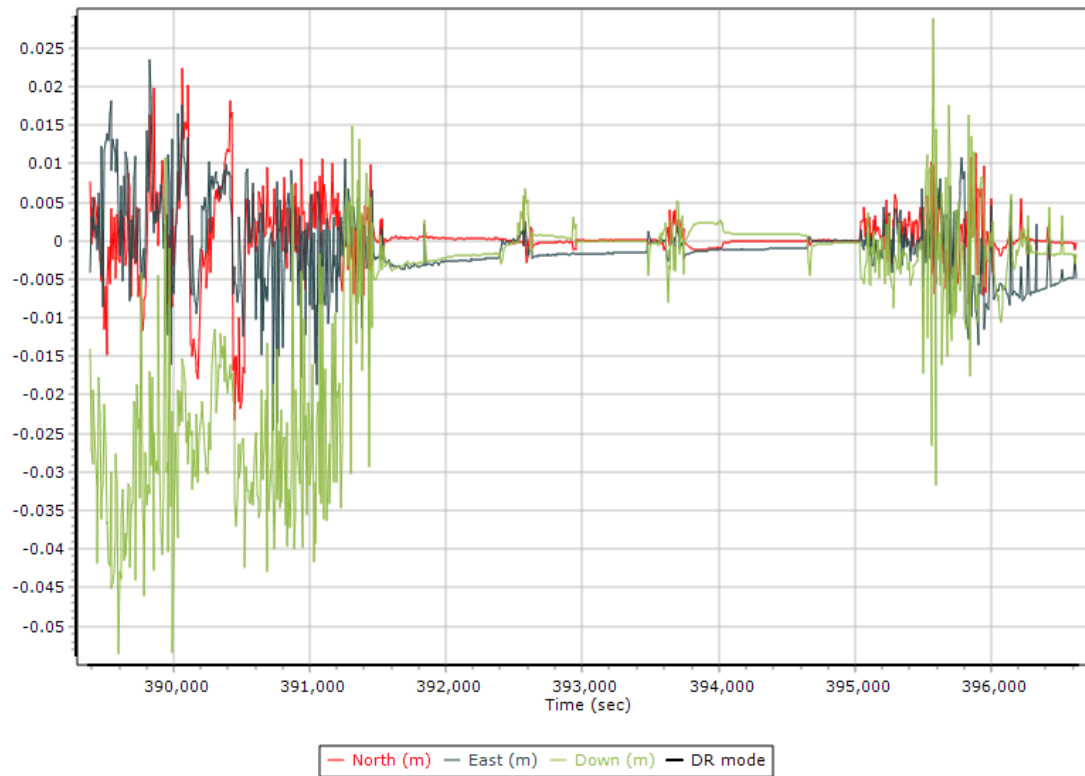
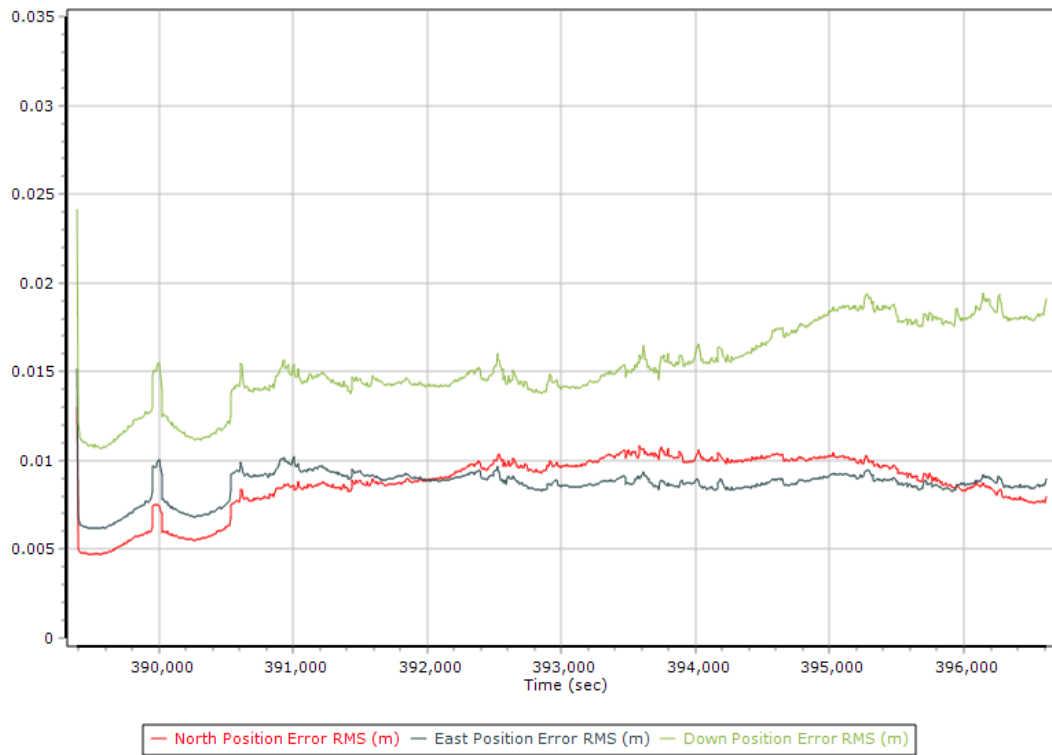
RBV18347A

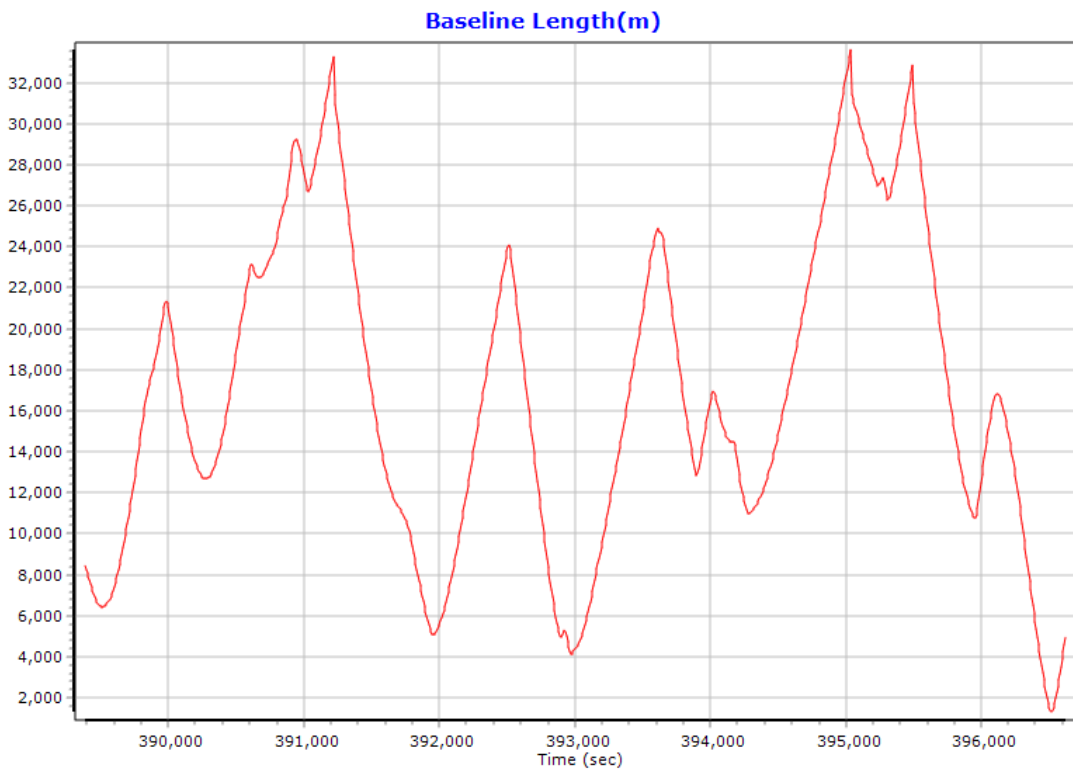
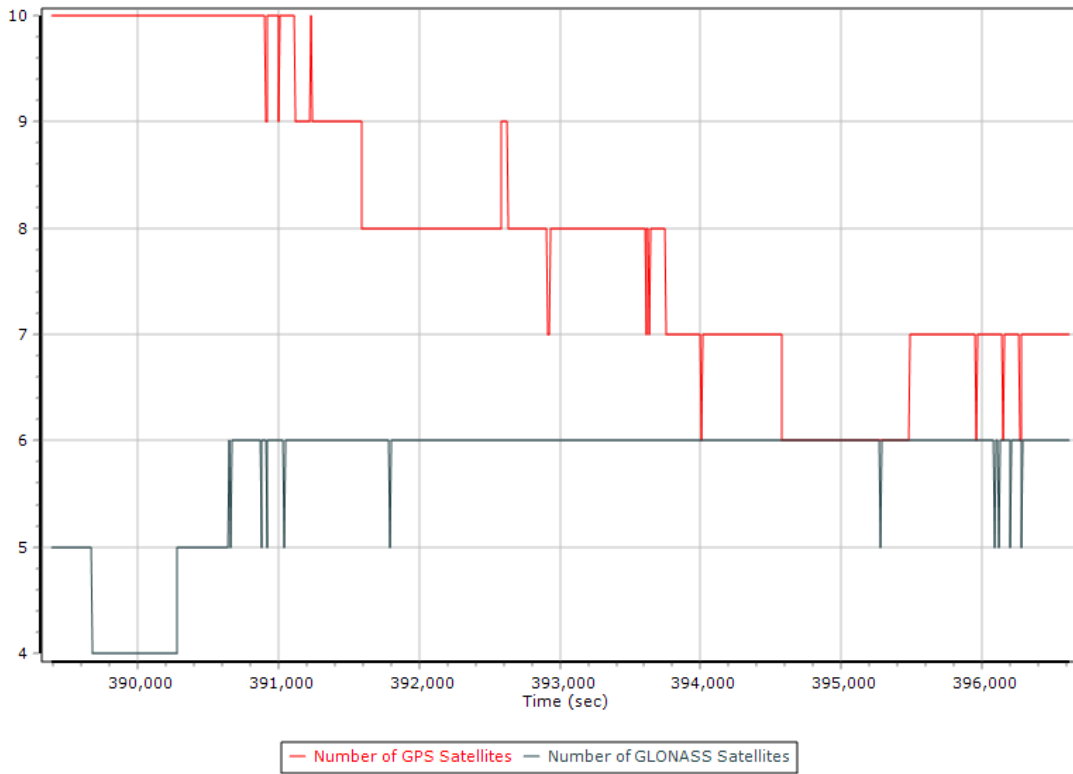


Reference to IMU Lever Arm		Reference to IMU Mounting Angles	
X	<input type="text" value="0.000 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="0.000 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="0.000 m"/>	Z	<input type="text" value="0.000 deg"/>
Reference to Primary GNSS Lever Arm		Aircraft to Reference Mounting Angles	
X	<input type="text" value="-0.024 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.001 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.742 m"/>	Z	<input type="text" value="0.000 deg"/>
Standard Deviation 			
<input type="radio"/> <3cm <input type="radio"/> 10cm <input type="radio"/> 50cm <input type="radio"/> 1m <input type="radio"/> 10m			

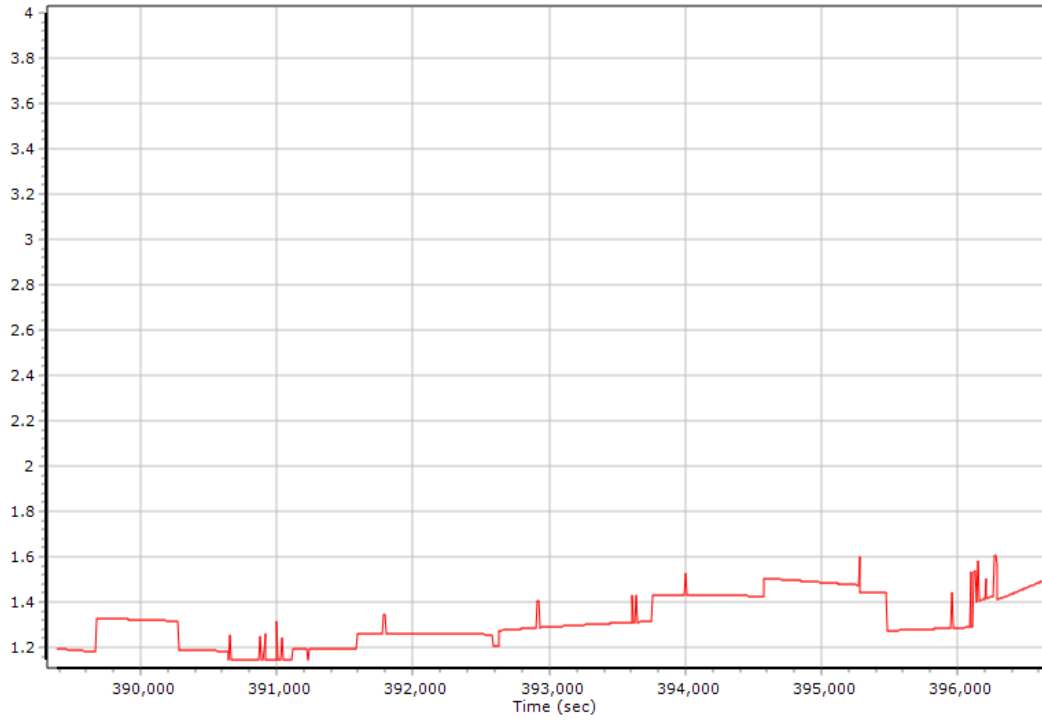
Timing									
Start	<input type="text" value="389385.904"/>								
End	<input type="text" value="396627.133"/>								
<input type="checkbox"/> Entire time interval									
<input checked="" type="checkbox"/> Seconds of start week									
UTC Offset	<input type="text" value="18.000"/>								
	<table border="1"><thead><tr><th>Data</th><th>Incr. (sec)</th></tr></thead><tbody><tr><td>Output Record</td><td>0.005000</td></tr><tr><td>IMU</td><td>0.005000</td></tr><tr><td>Primary GNSS</td><td>1.000000</td></tr></tbody></table>	Data	Incr. (sec)	Output Record	0.005000	IMU	0.005000	Primary GNSS	1.000000
Data	Incr. (sec)								
Output Record	0.005000								
IMU	0.005000								
Primary GNSS	1.000000								



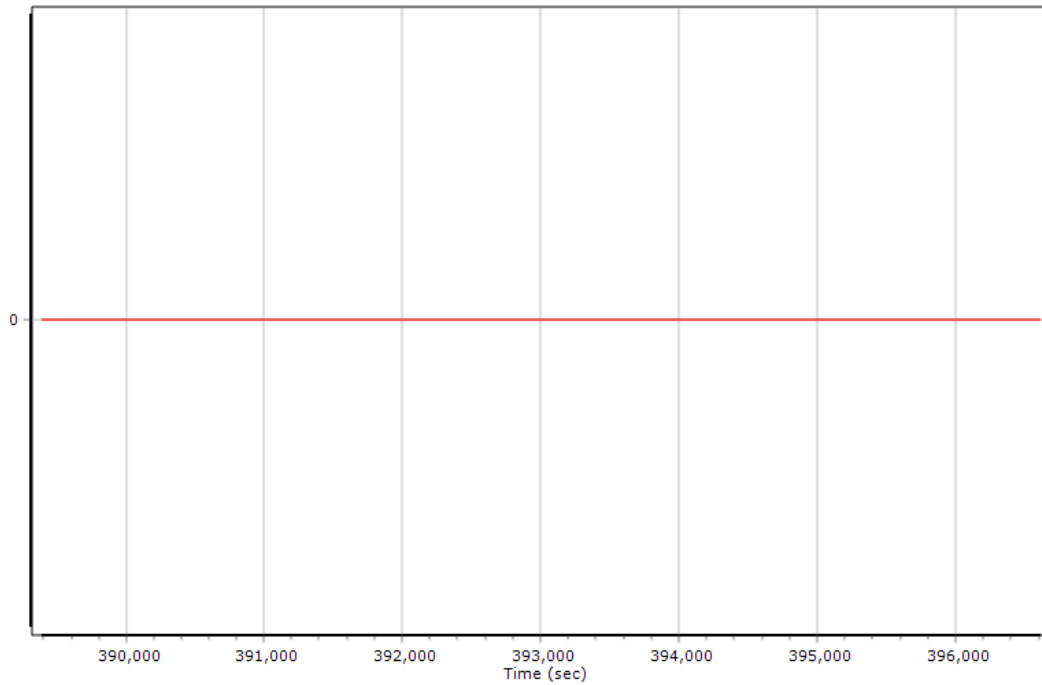




PDOP

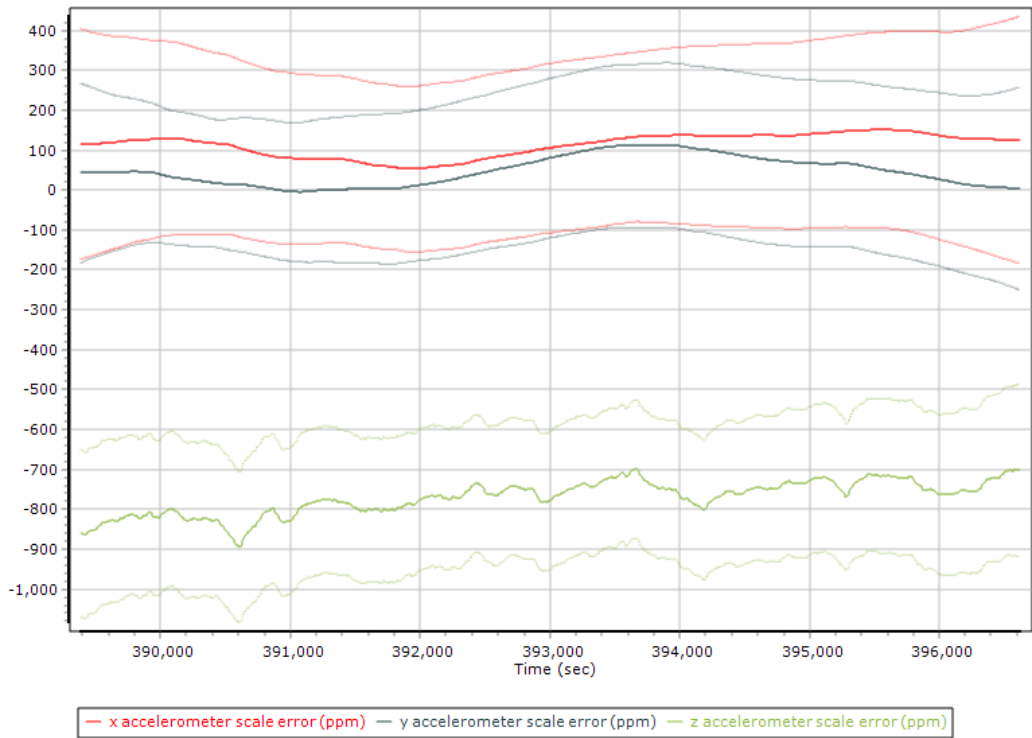
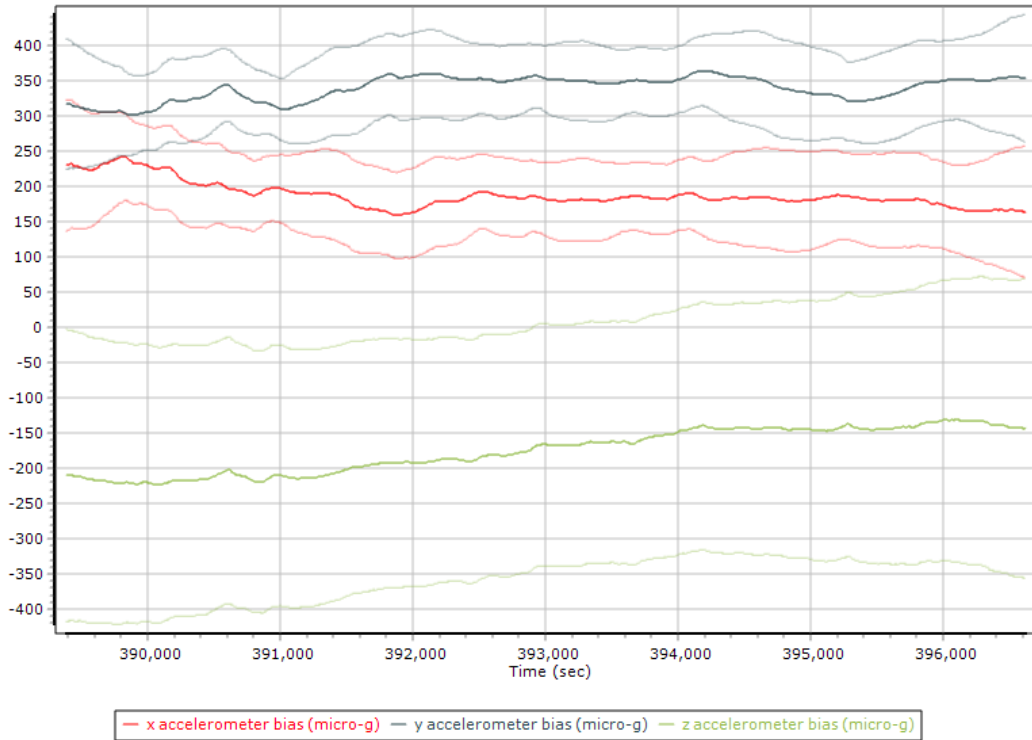


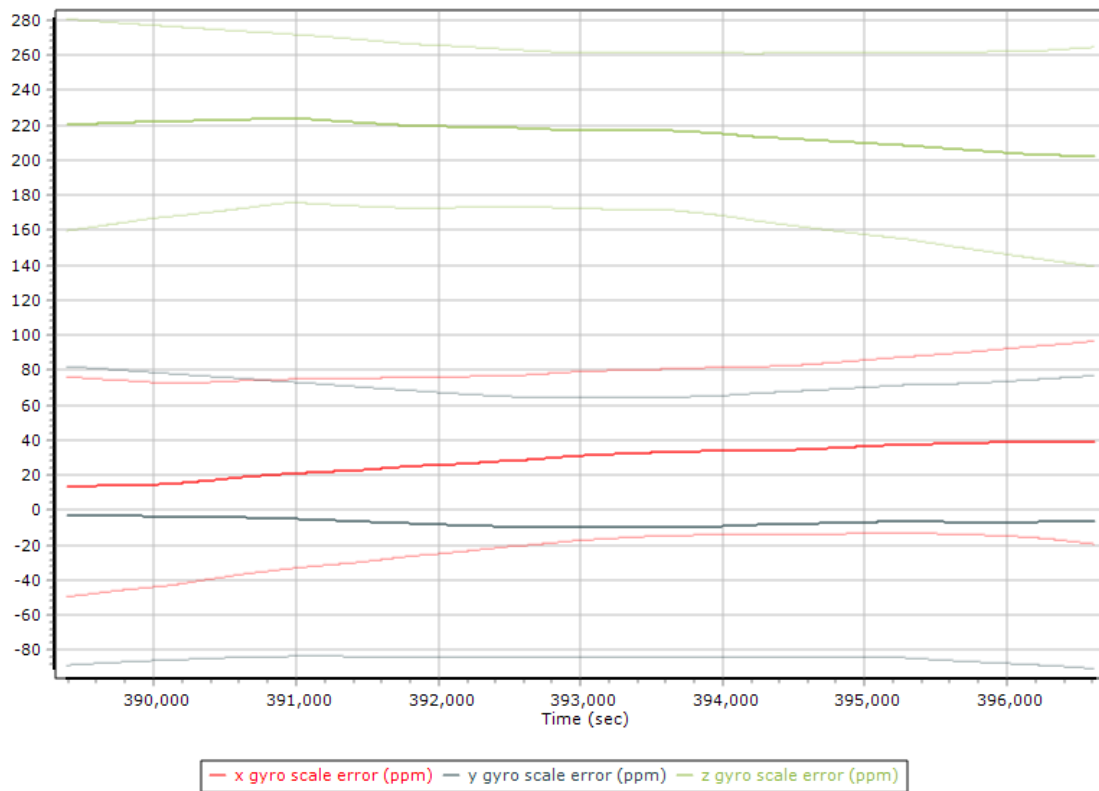
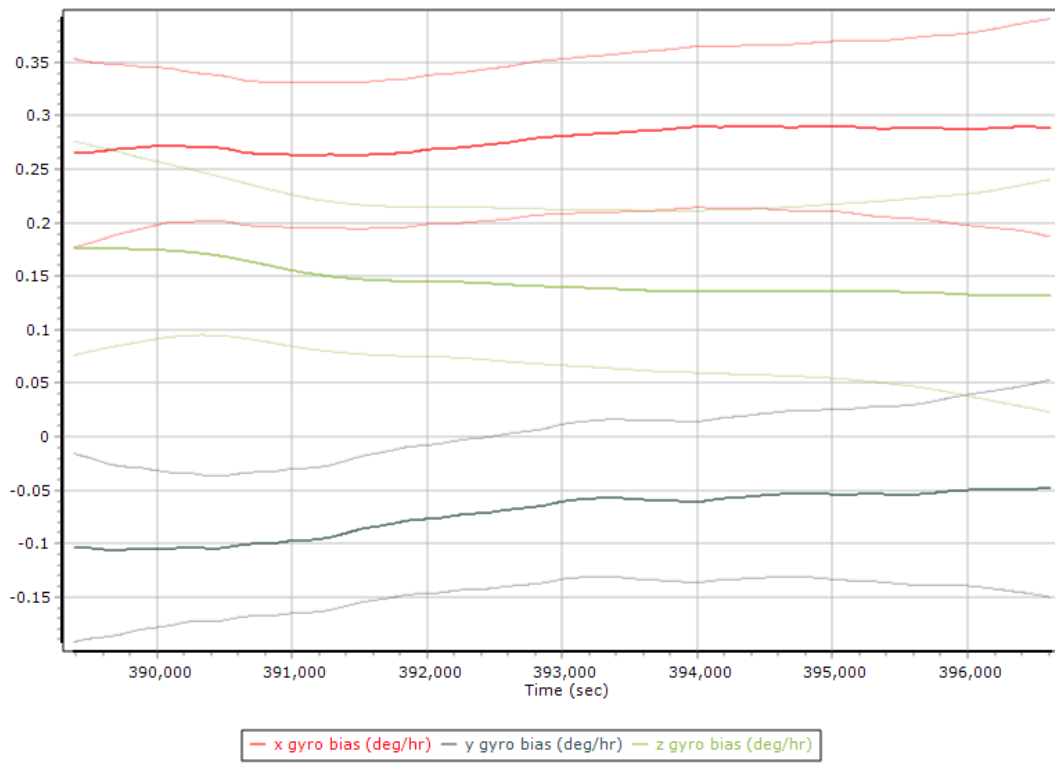
Processing Mode



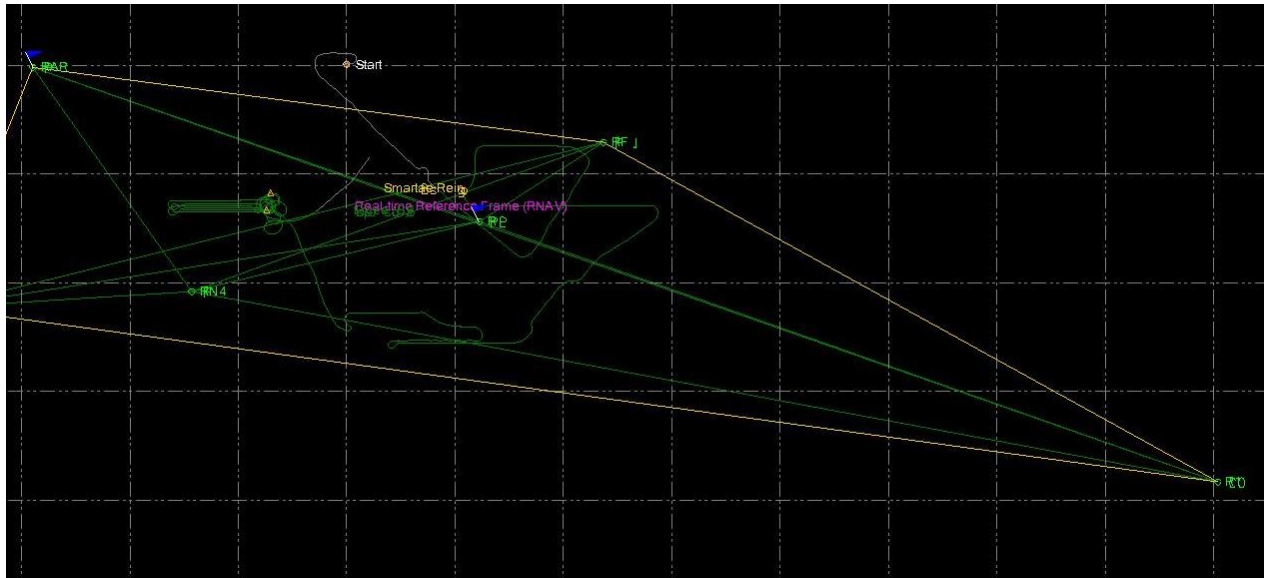
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





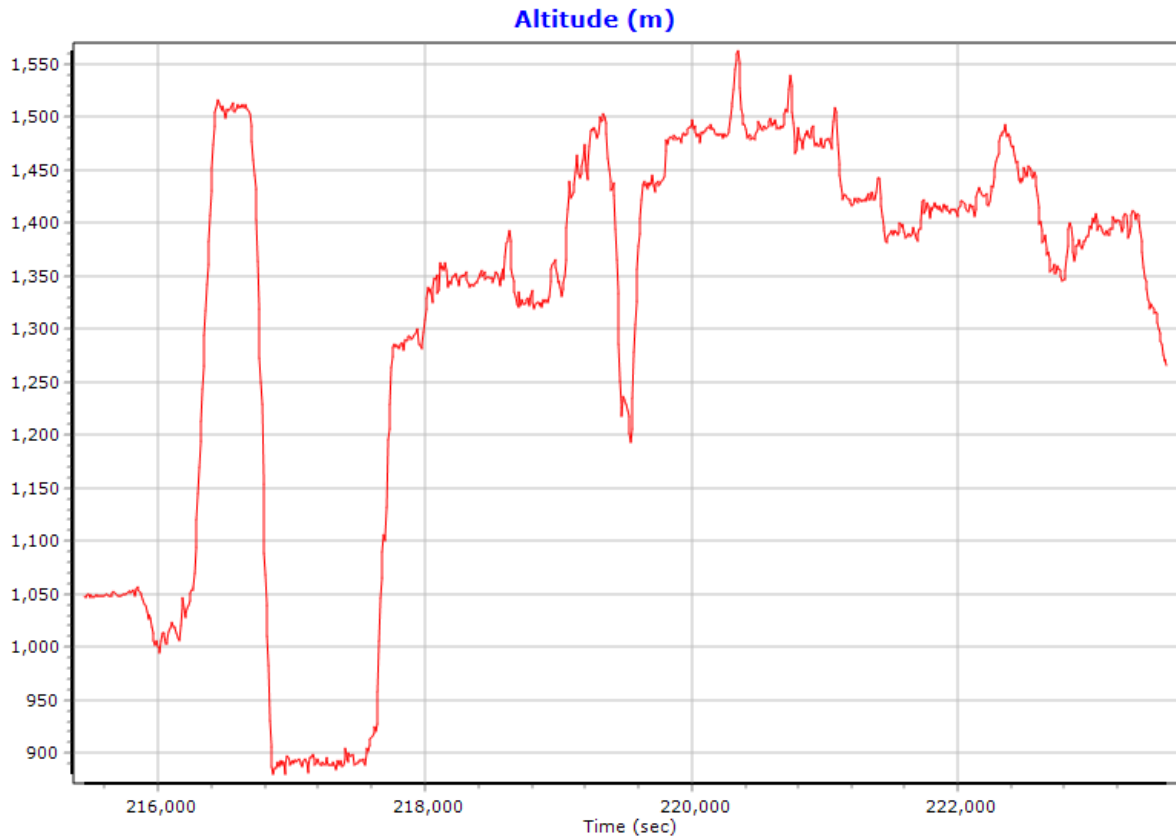
RBV18352A

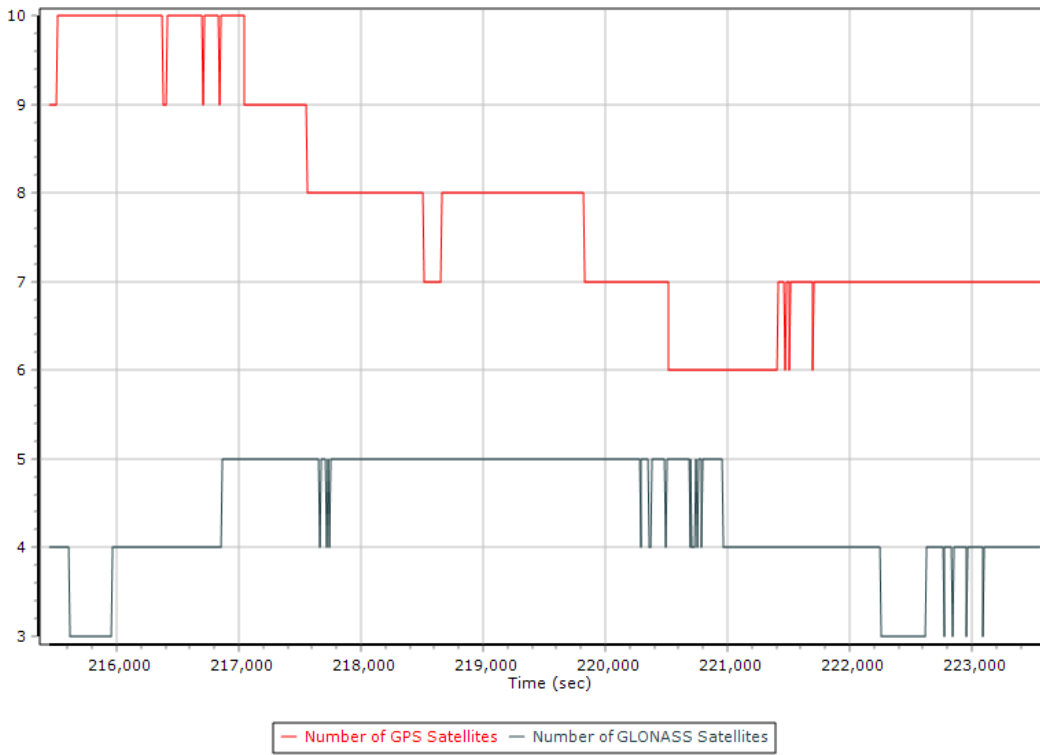
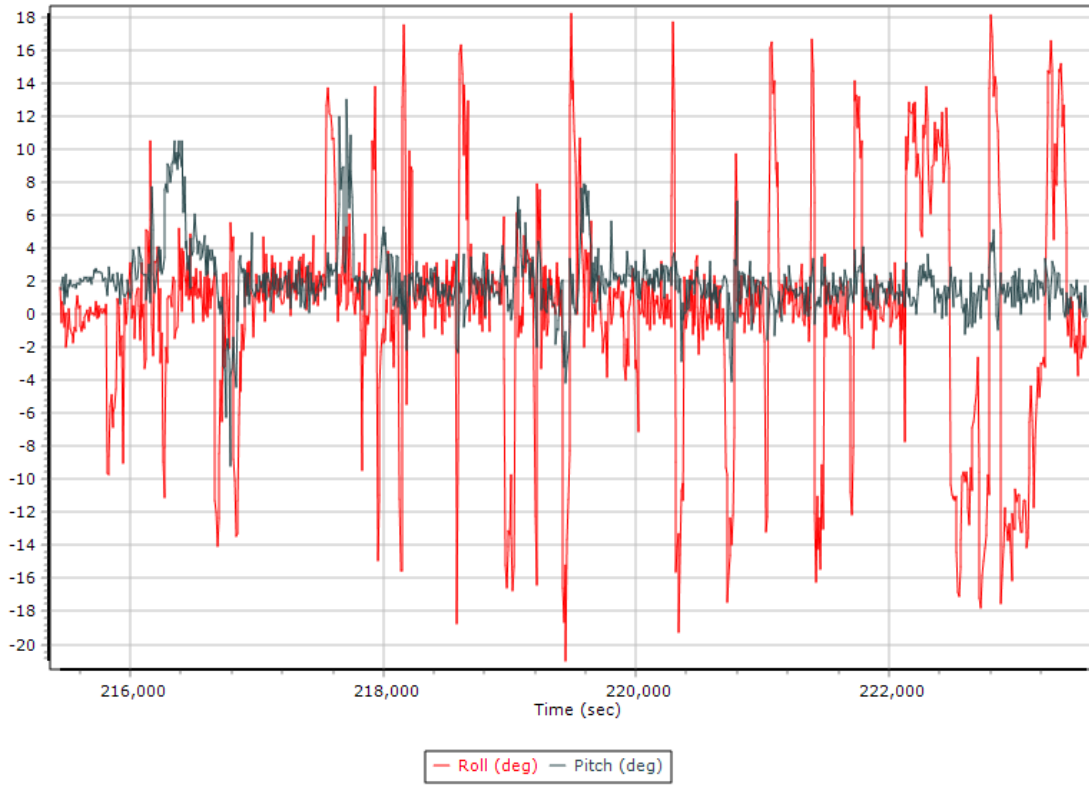


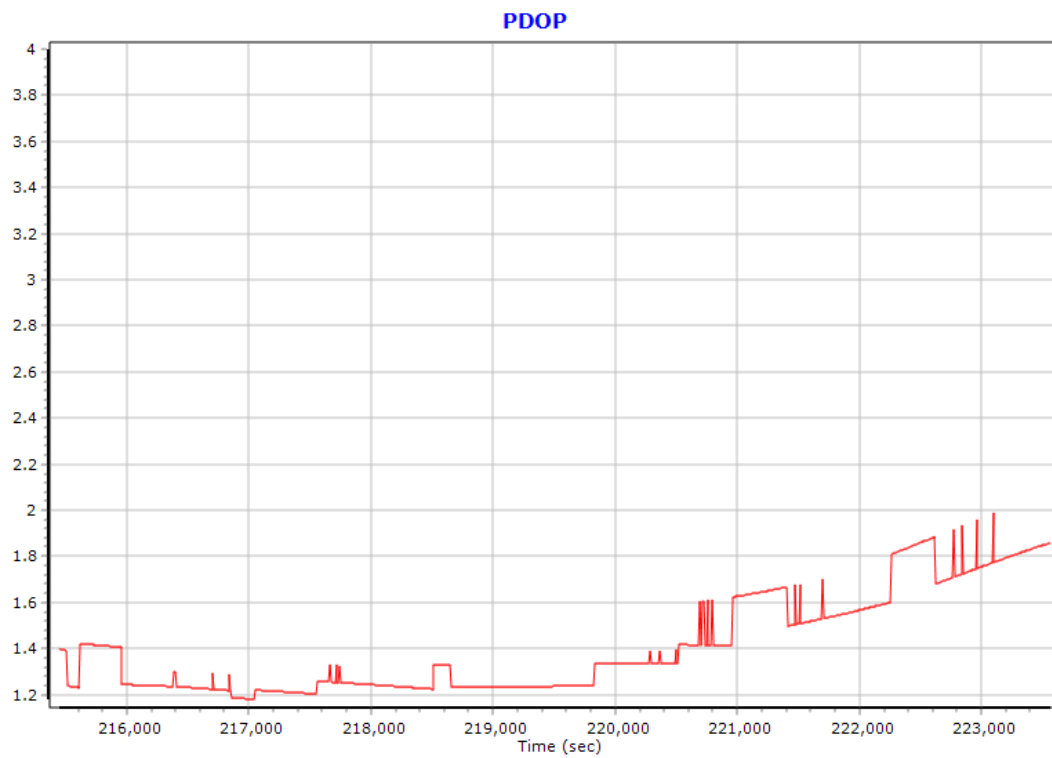
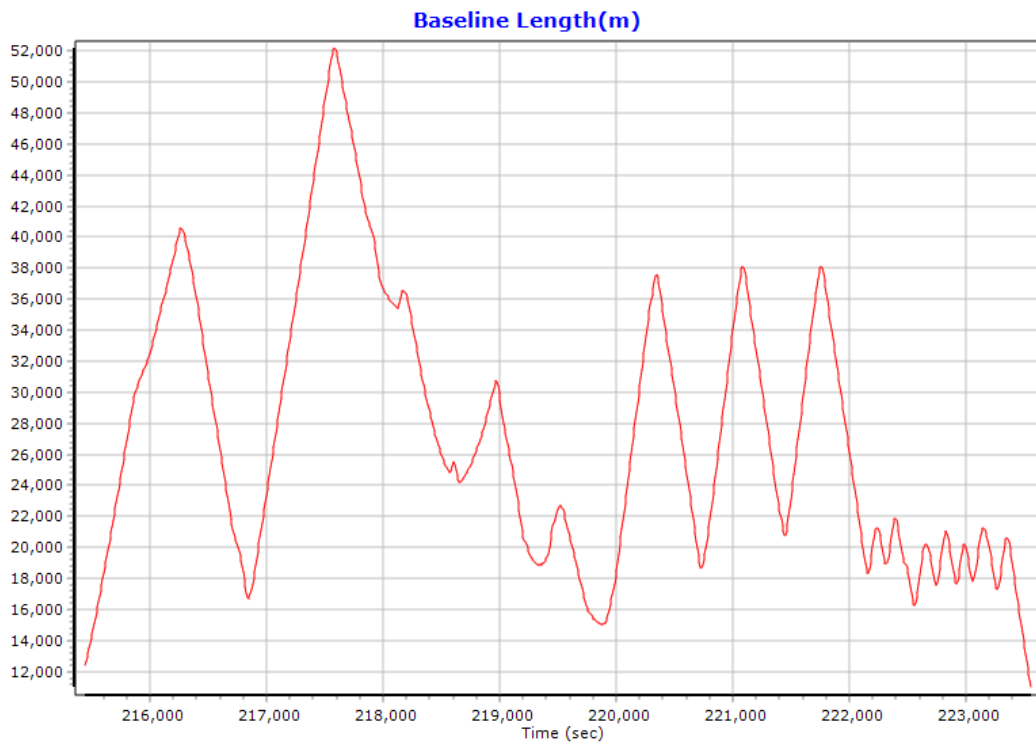
Reference to IMU Lever Arm		Reference to IMU Mounting Angles	
X	<input type="text" value="0.000 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="0.000 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="0.000 m"/>	Z	<input type="text" value="0.000 deg"/>
Reference to Primary GNSS Lever Arm		Aircraft to Reference Mounting Angles	
X	<input type="text" value="-0.024 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.001 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.742 m"/>	Z	<input type="text" value="0.000 deg"/>
Standard Deviation			
<input type="range" value="0.03"/>			
<3cm 10cm 50cm 1m 10m			

Timing

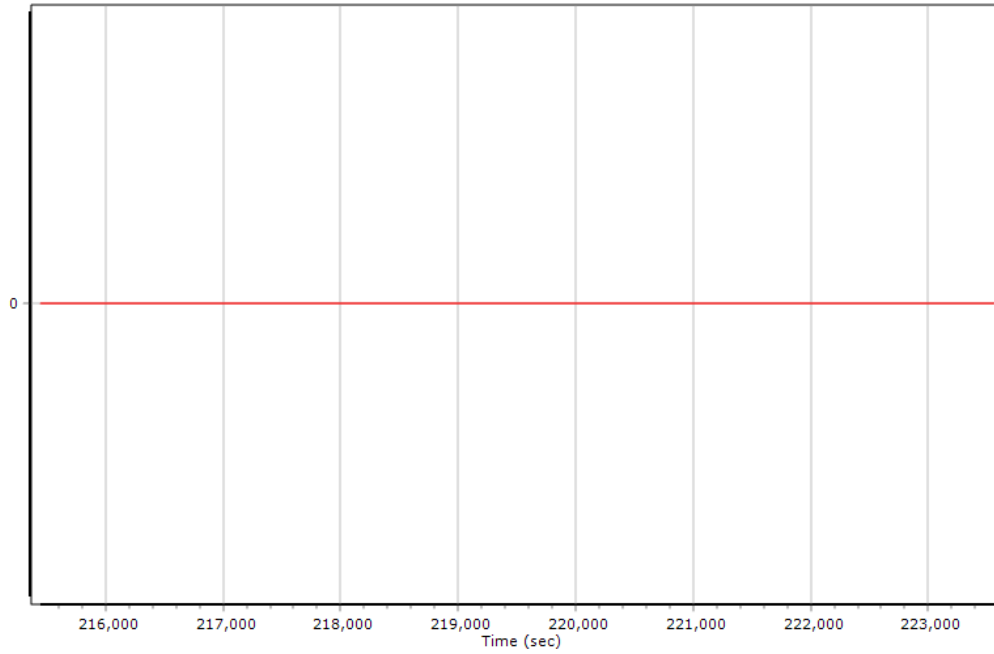
Start	215443.631	Data	Incr. (sec)
End	223568.766	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000





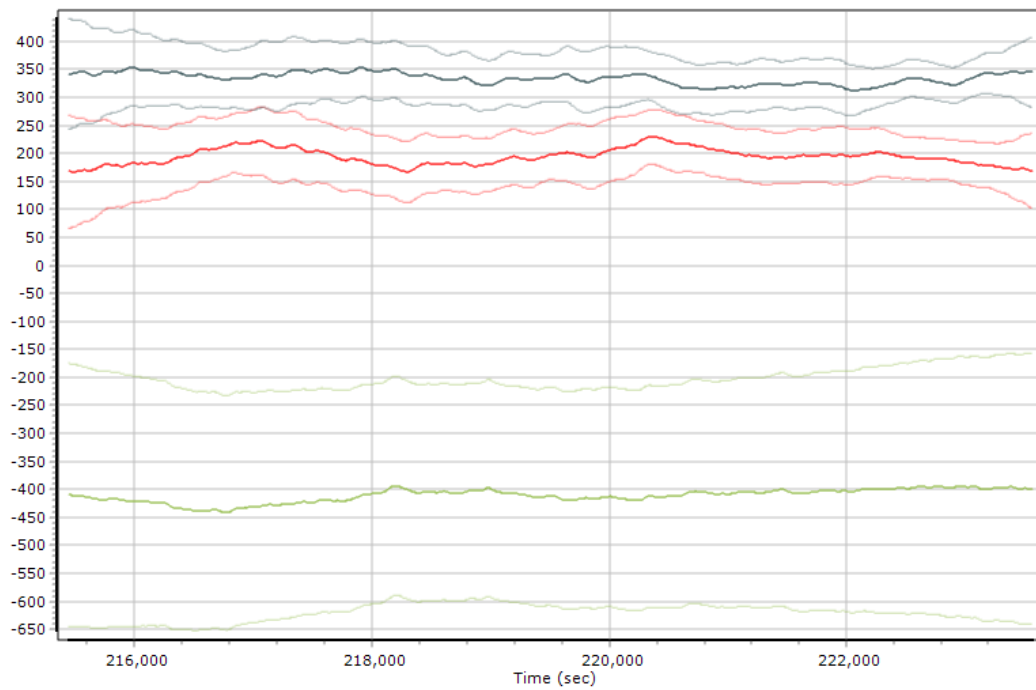


Processing Mode

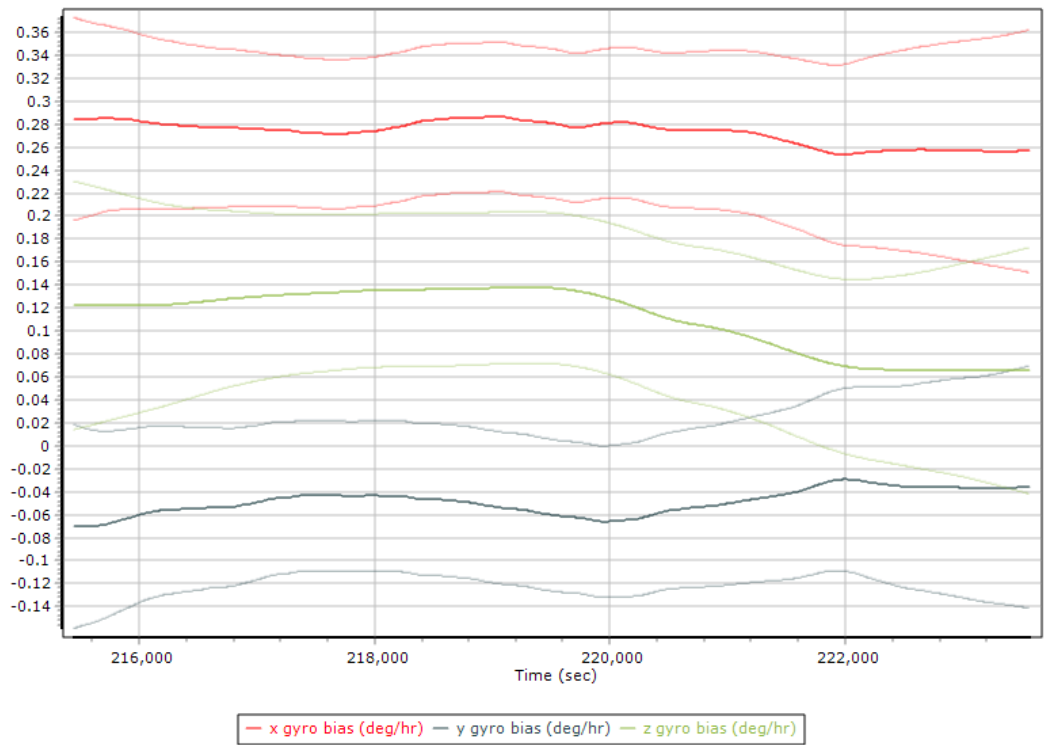
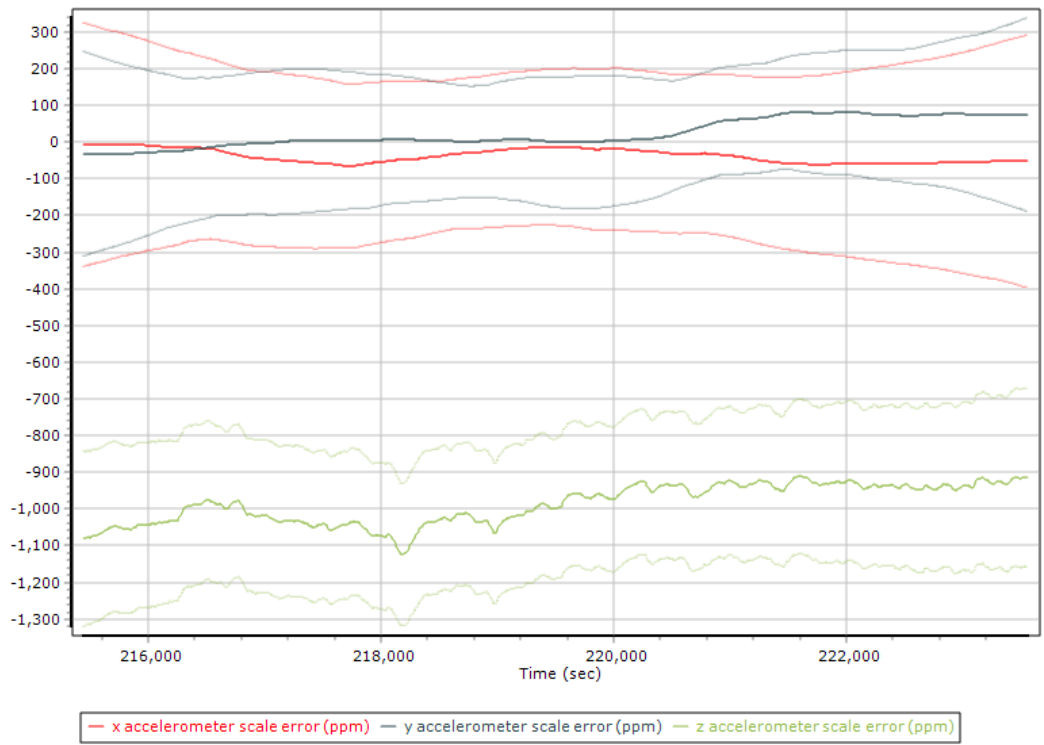


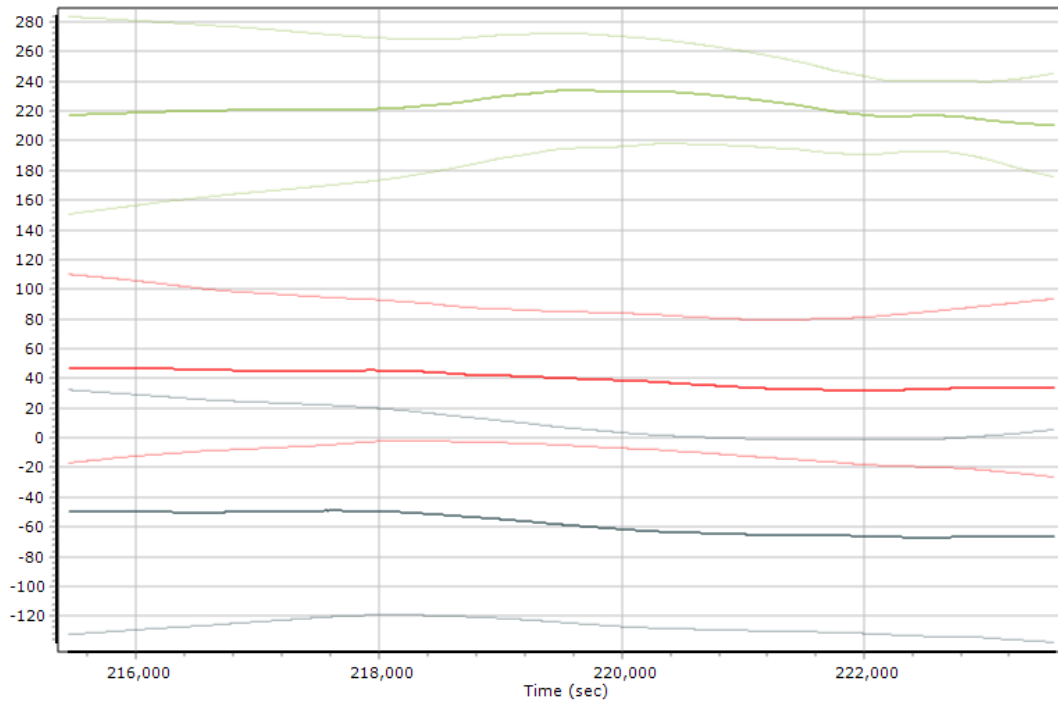
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors



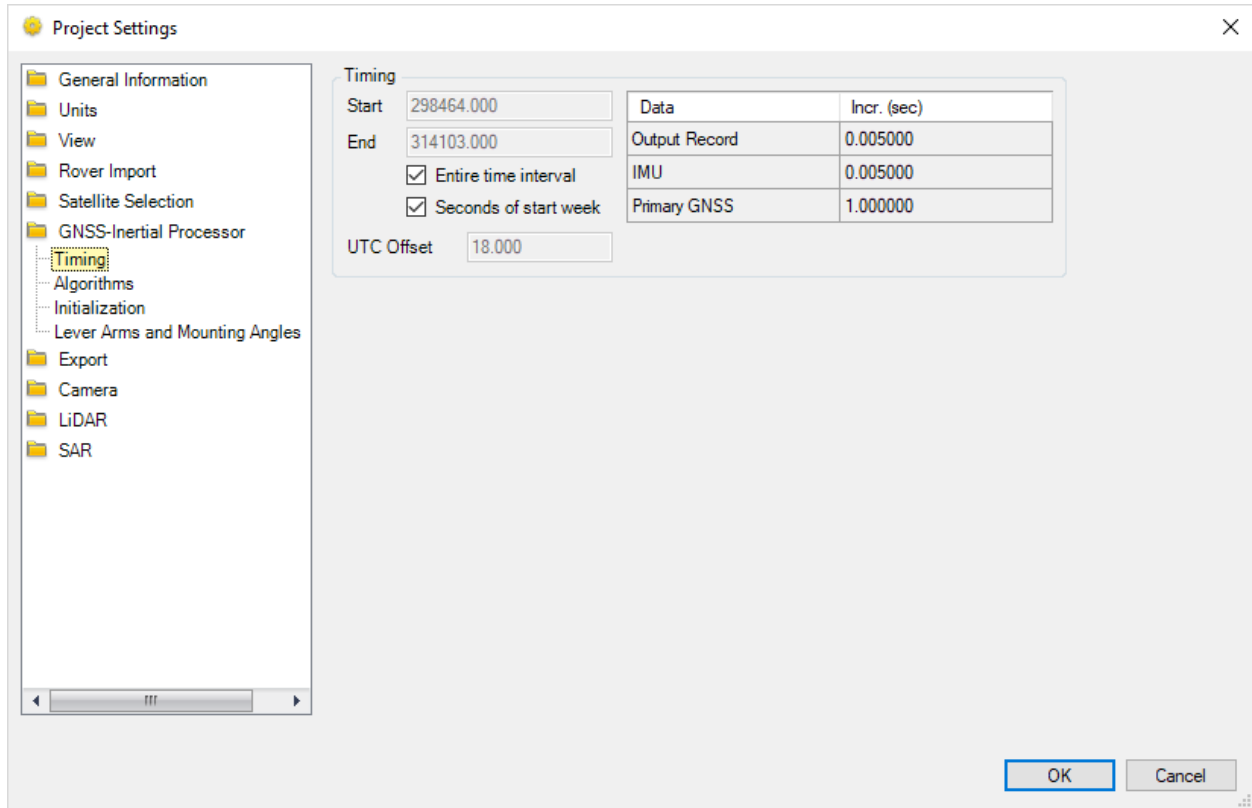
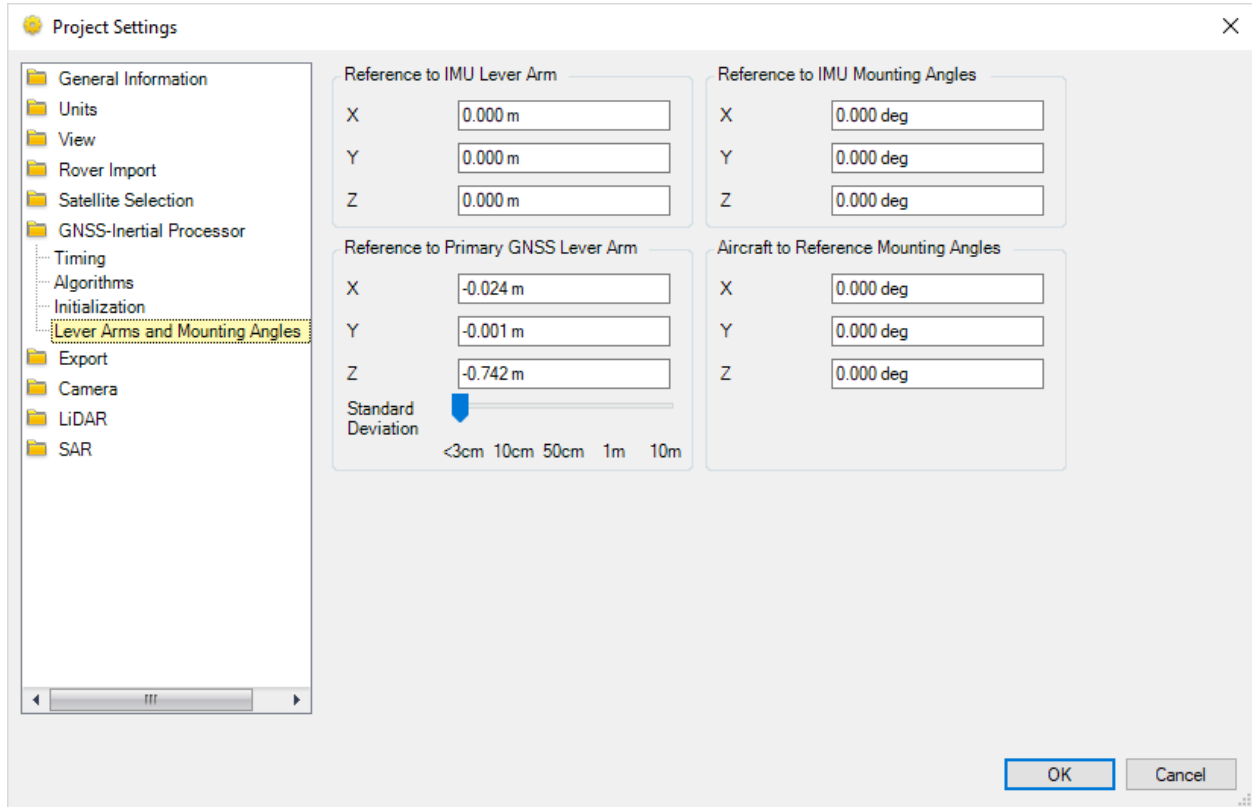
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)

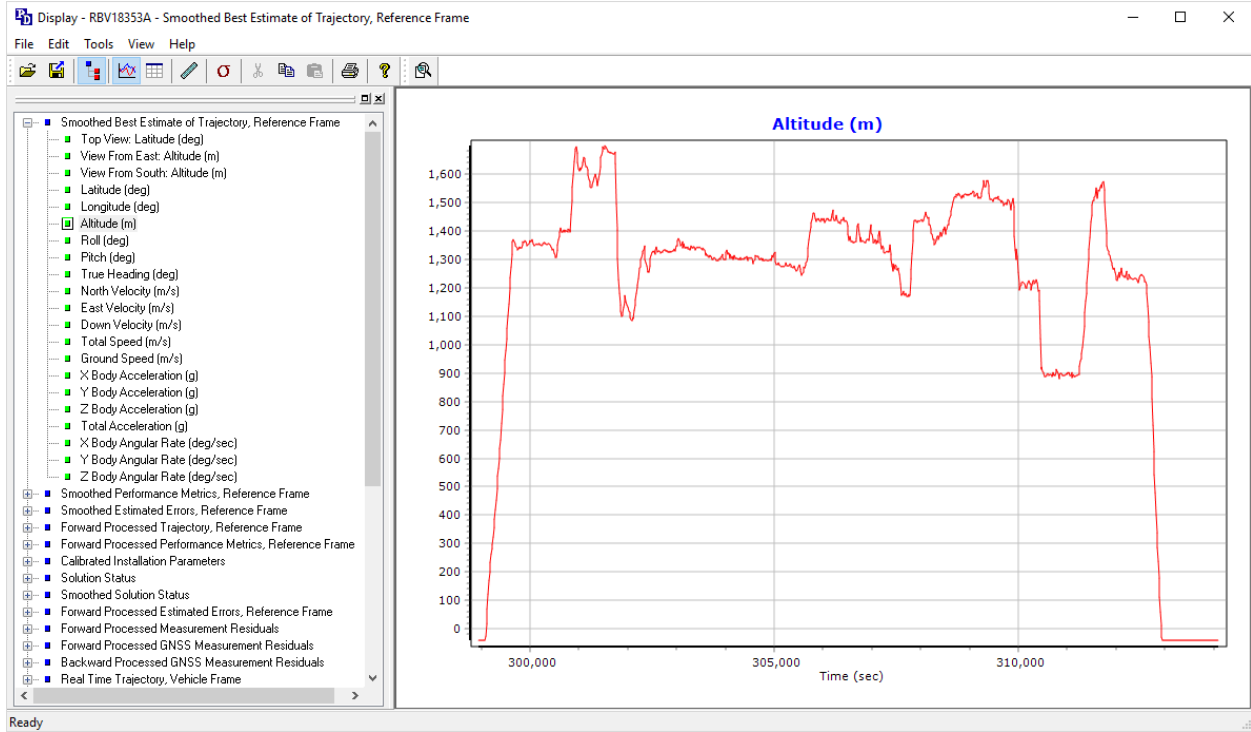


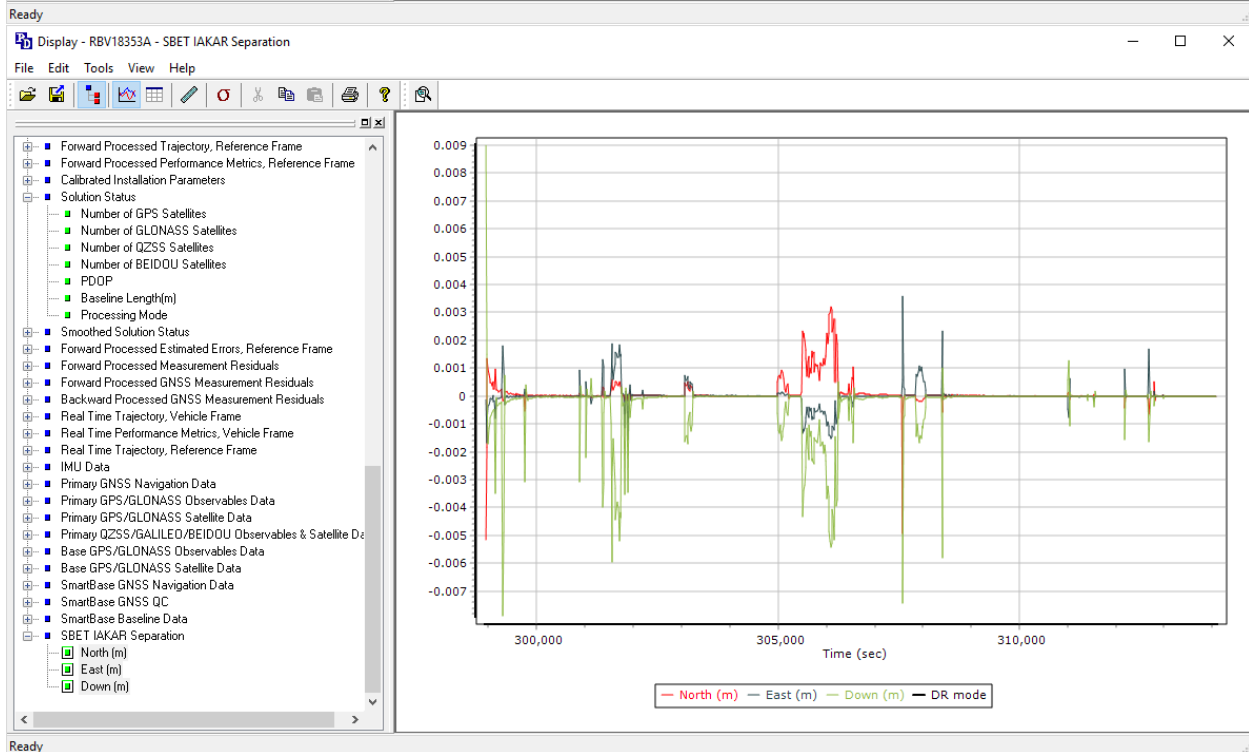
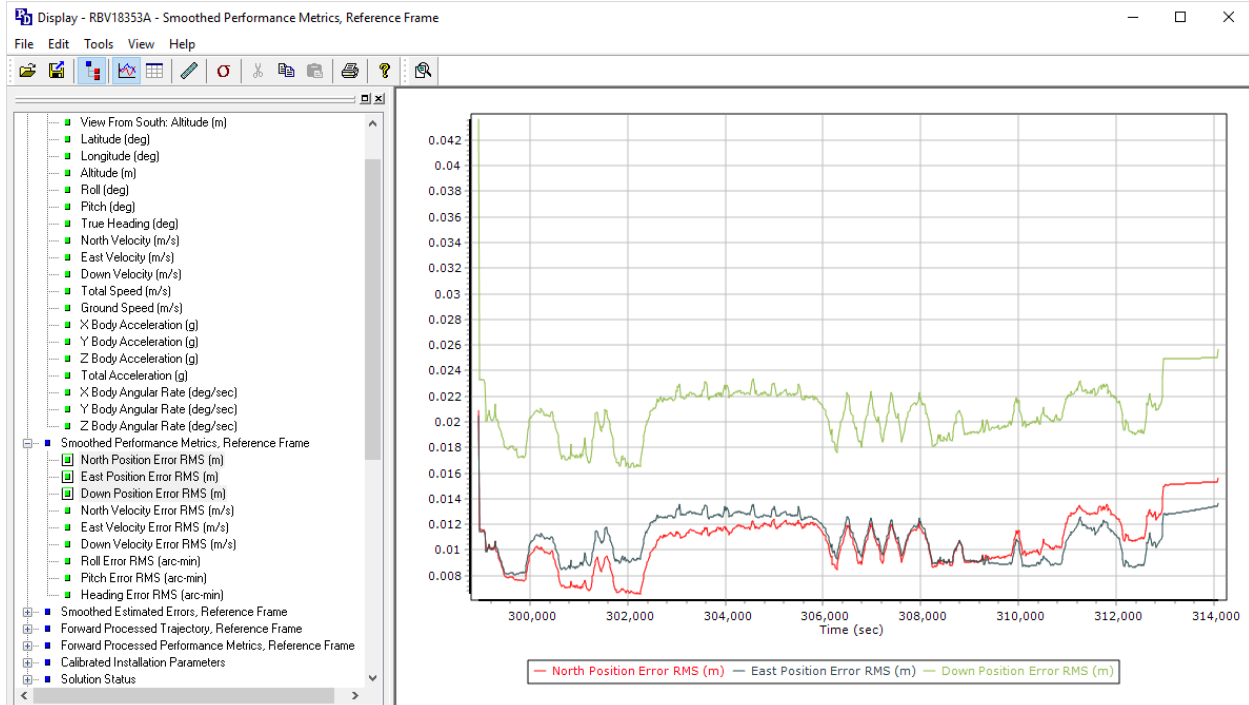


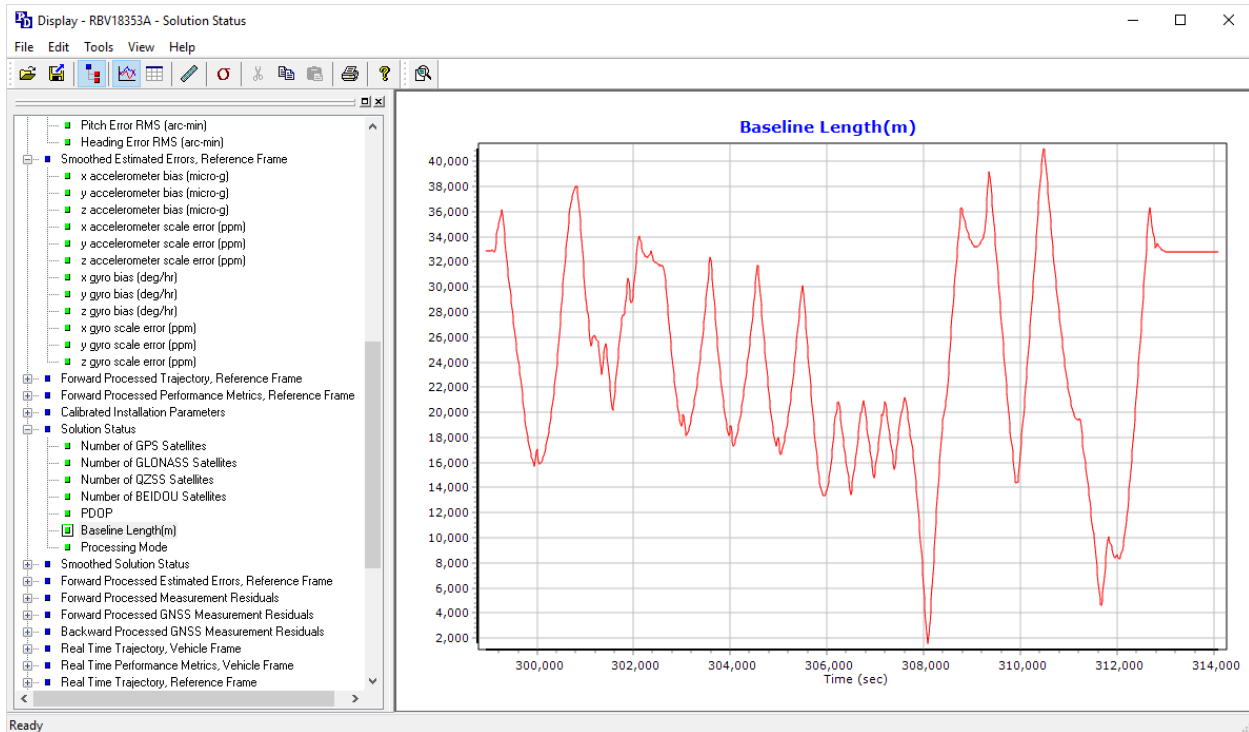
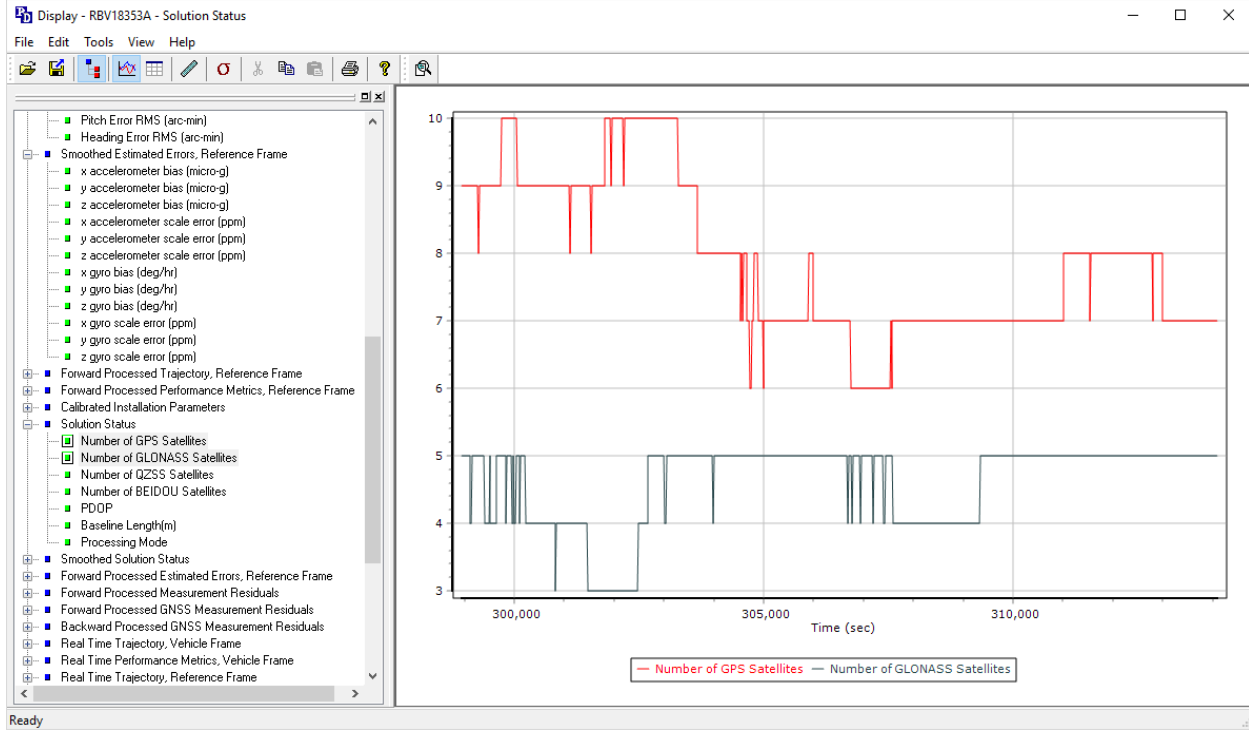
— x gyro scale error (ppm) — y gyro scale error (ppm) — z gyro scale error (ppm)

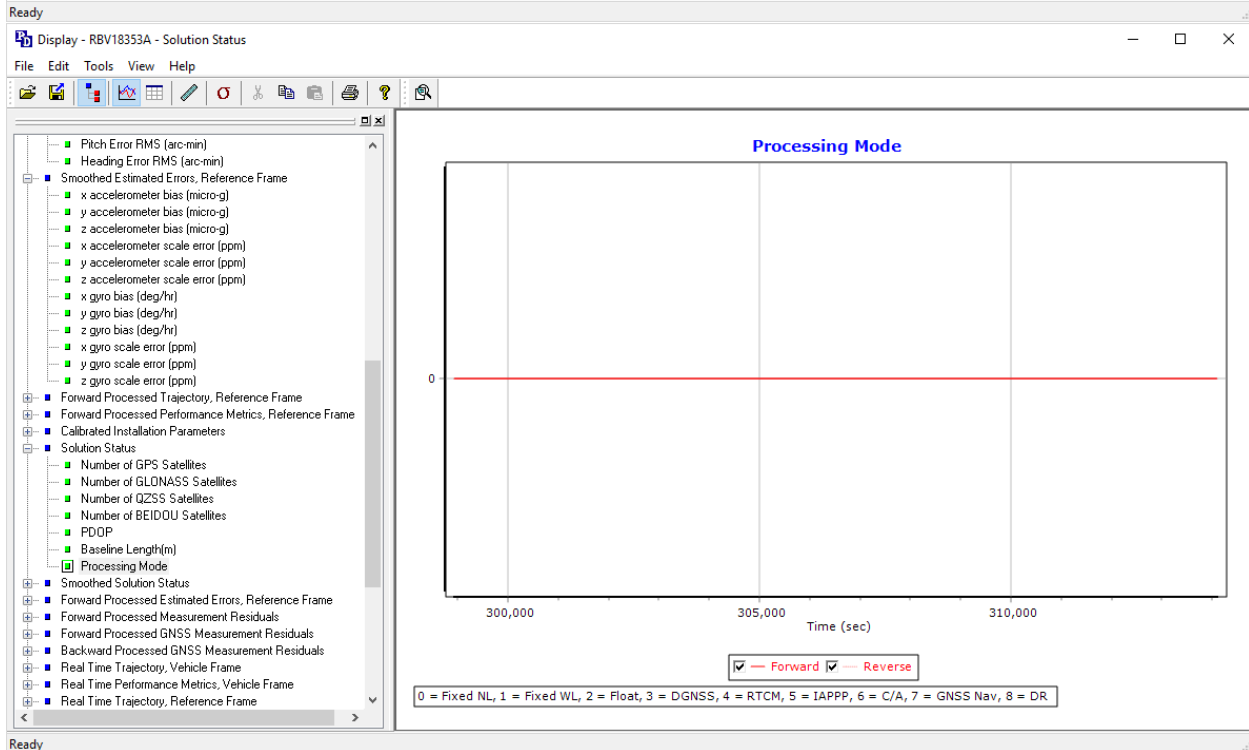
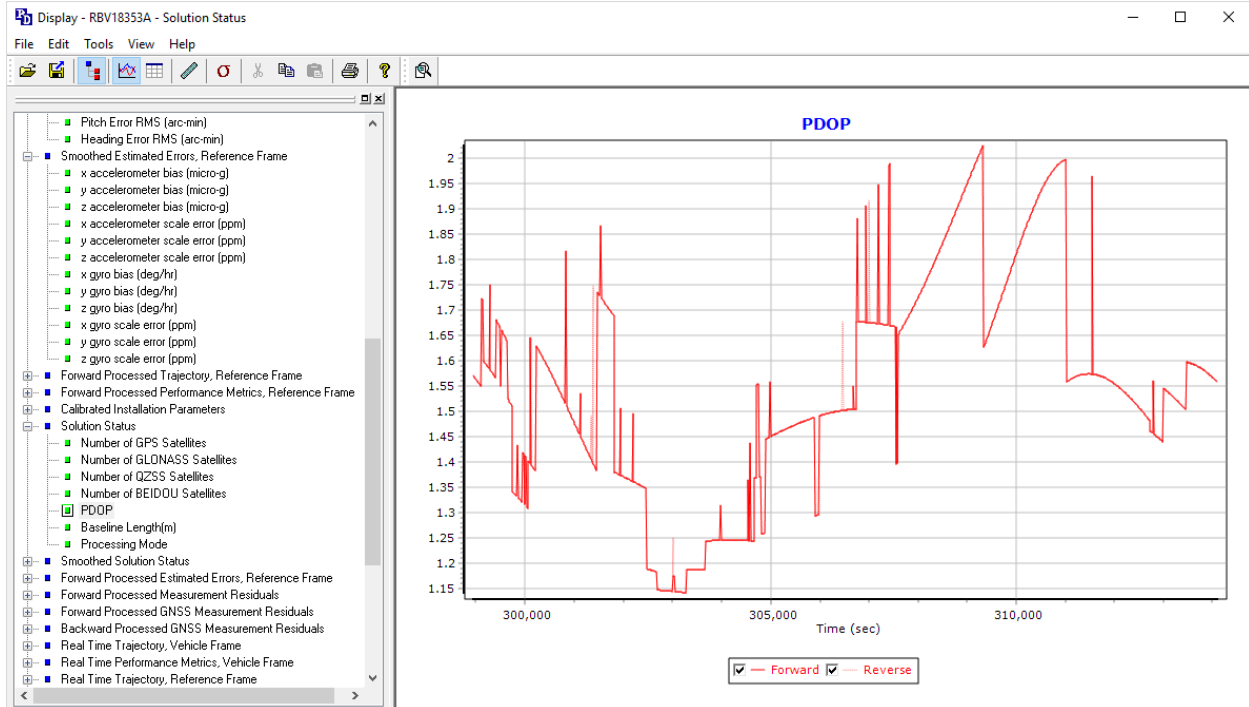
RBV18353A



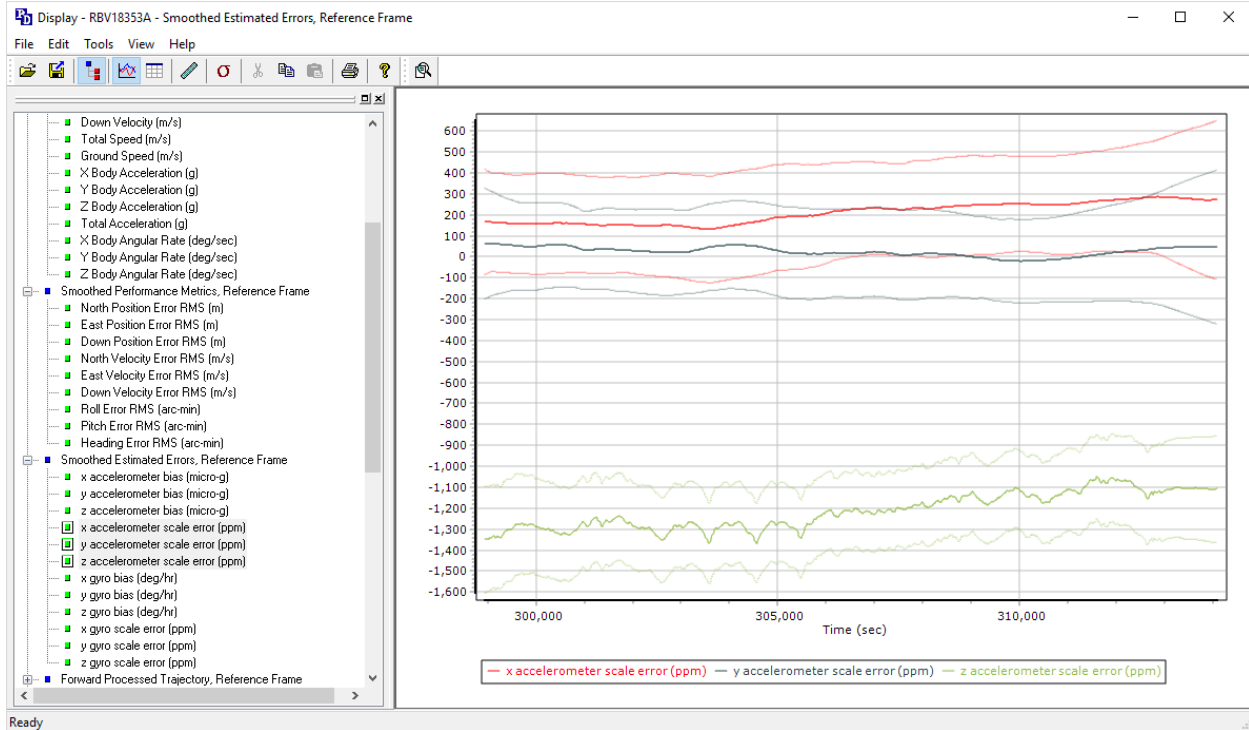
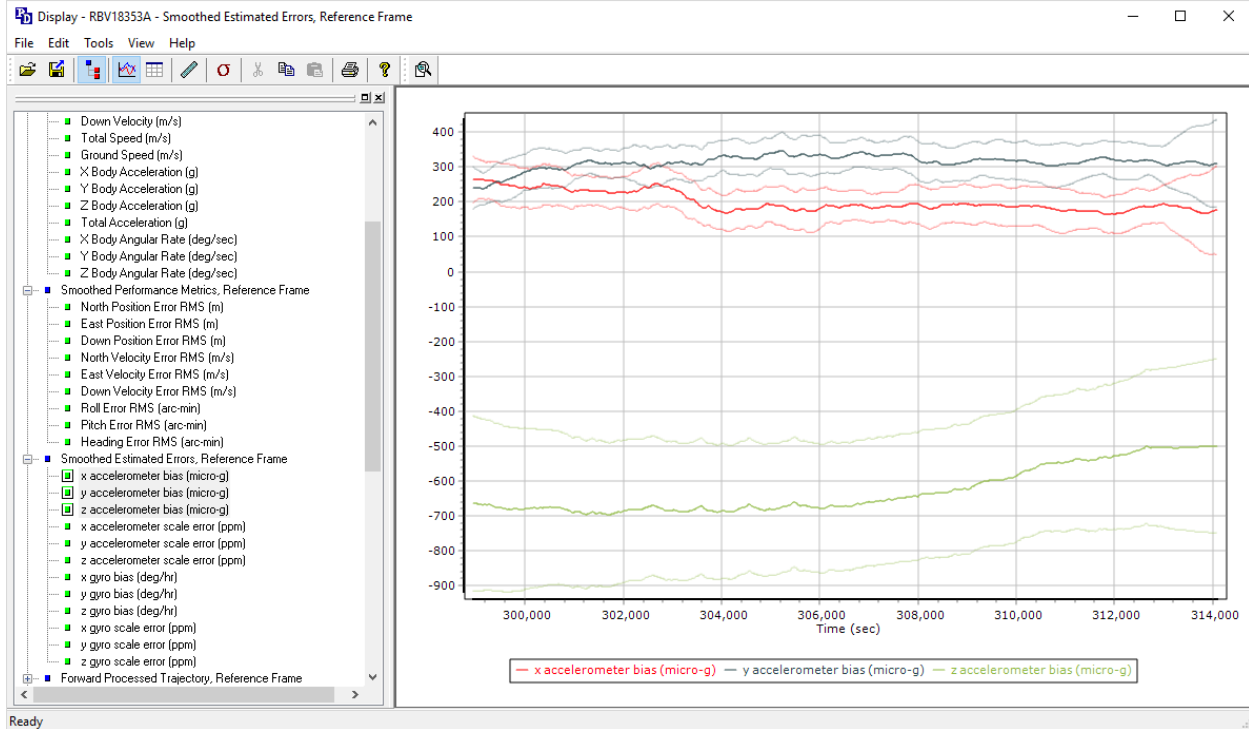


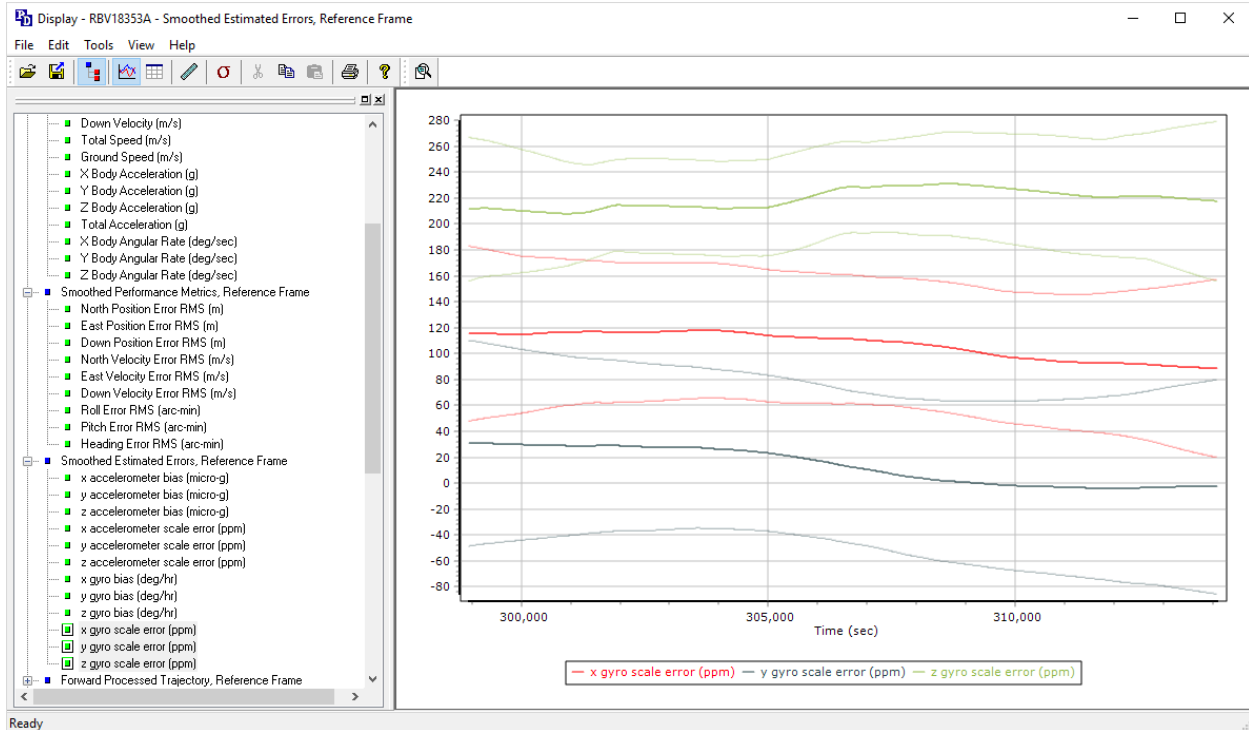
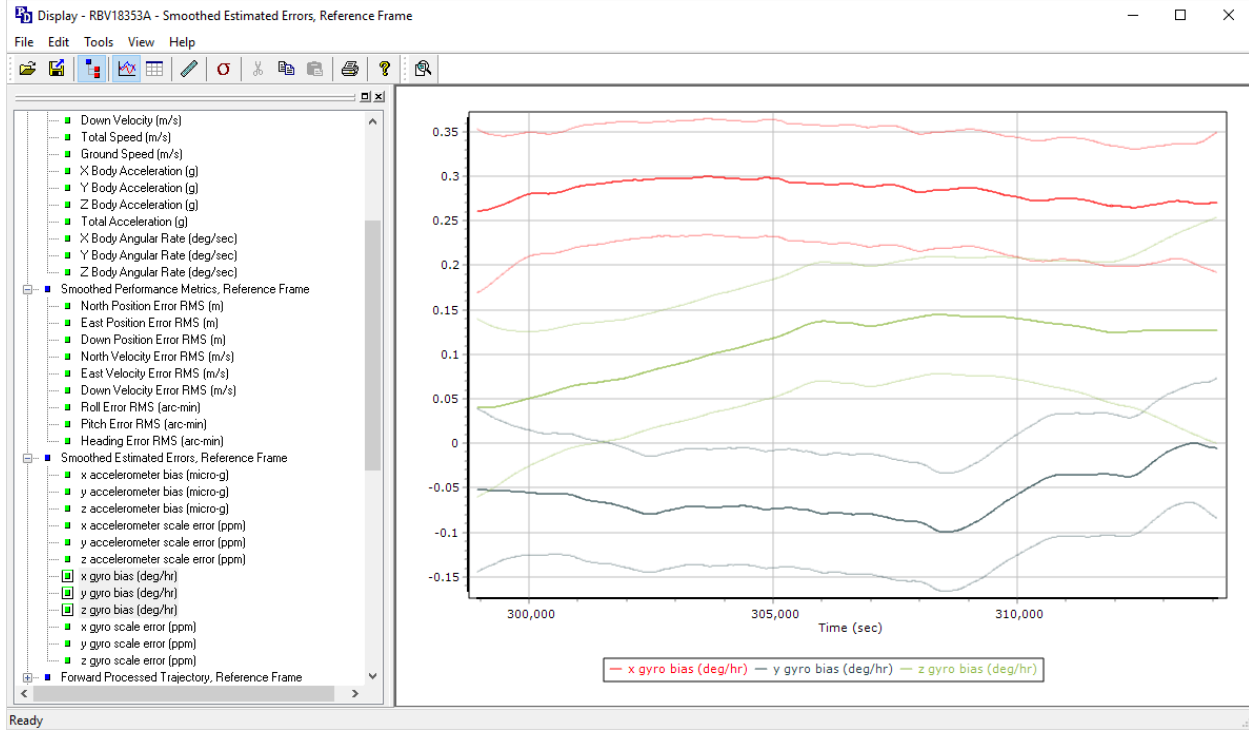




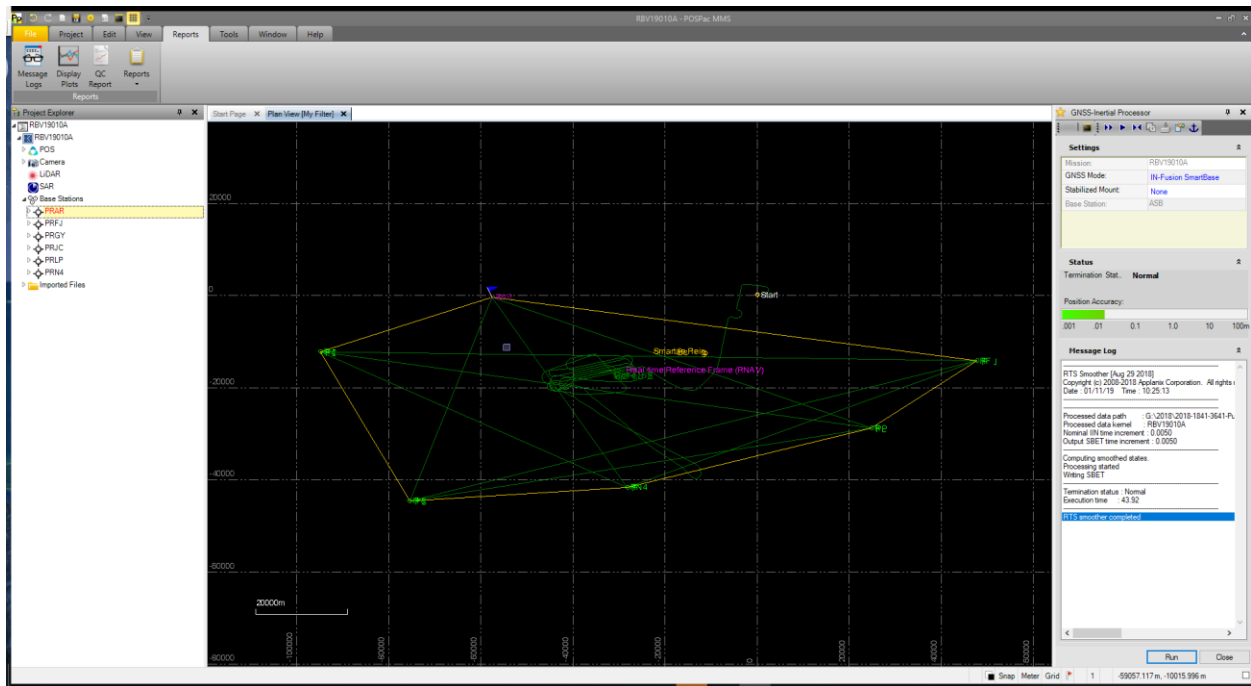


Sensor Errors





RBV19010A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNS-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: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 m	Z: 0.000 deg

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

OK Cancel

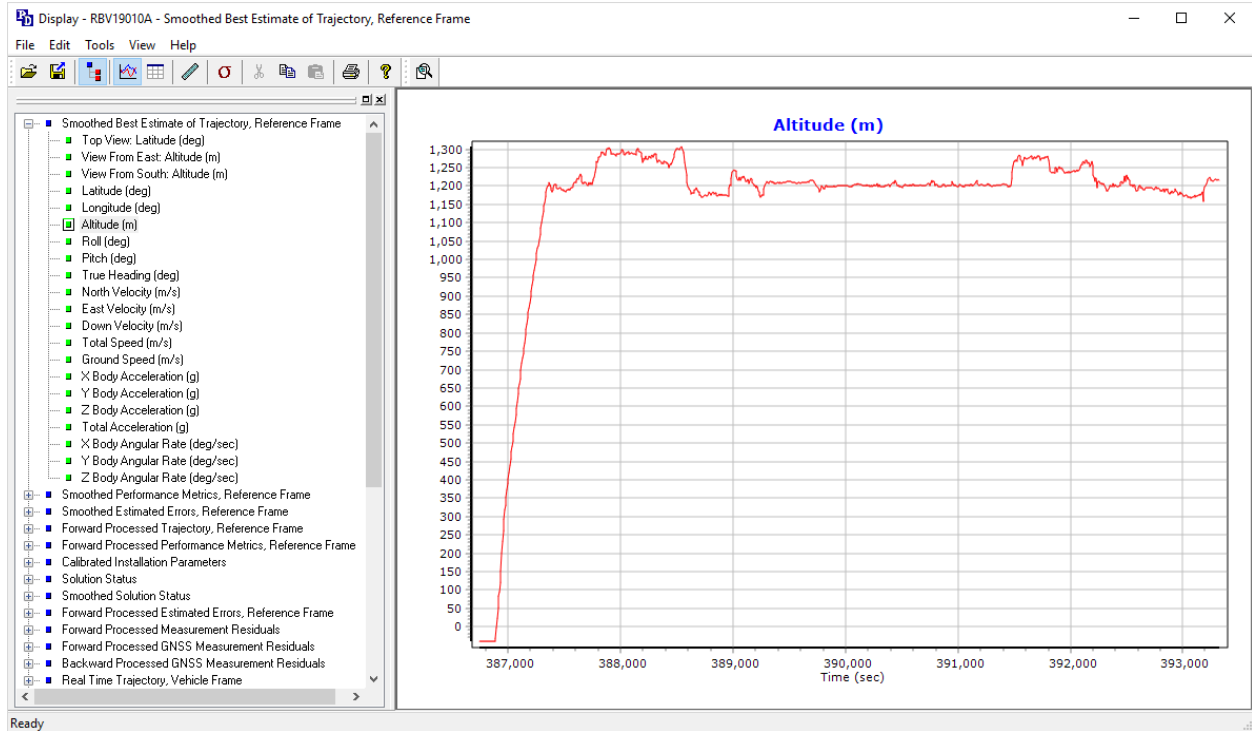
Project Settings

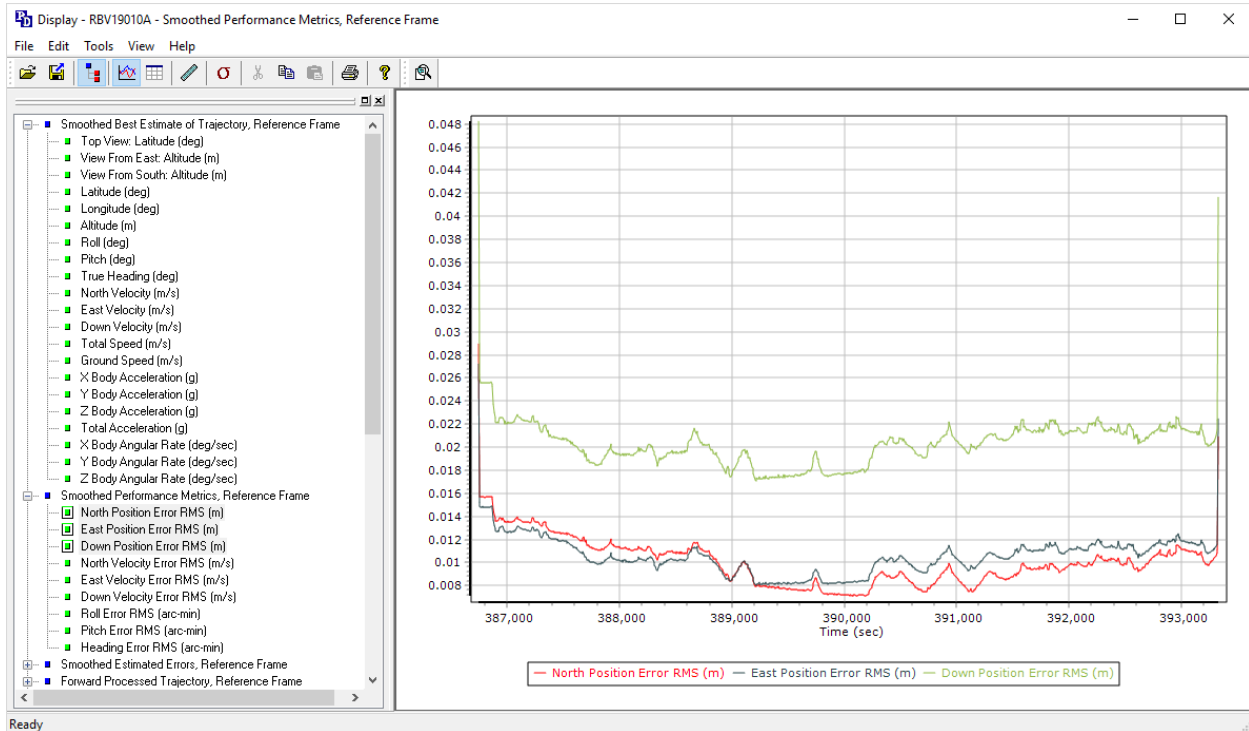
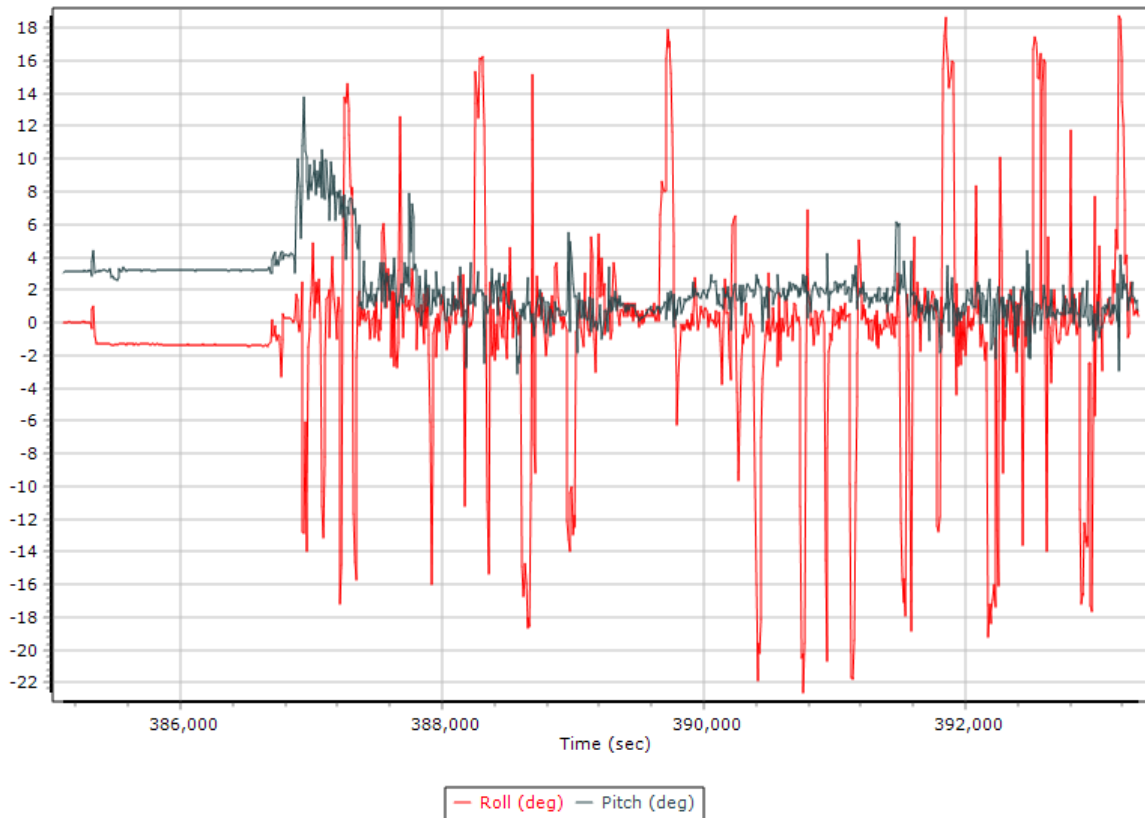
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
 Timing
 Algorithms
 Initialization
 Lever Arms and Mounting Angles
Export
Camera
LiDAR
SAR

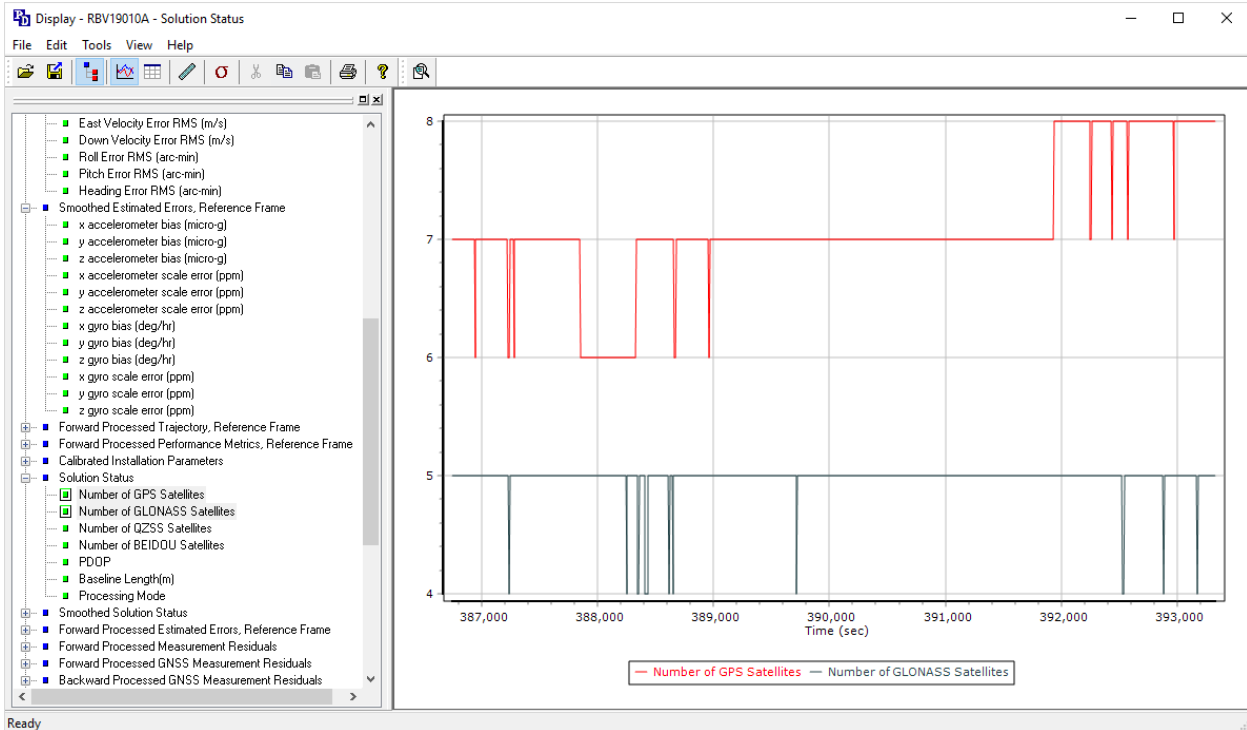
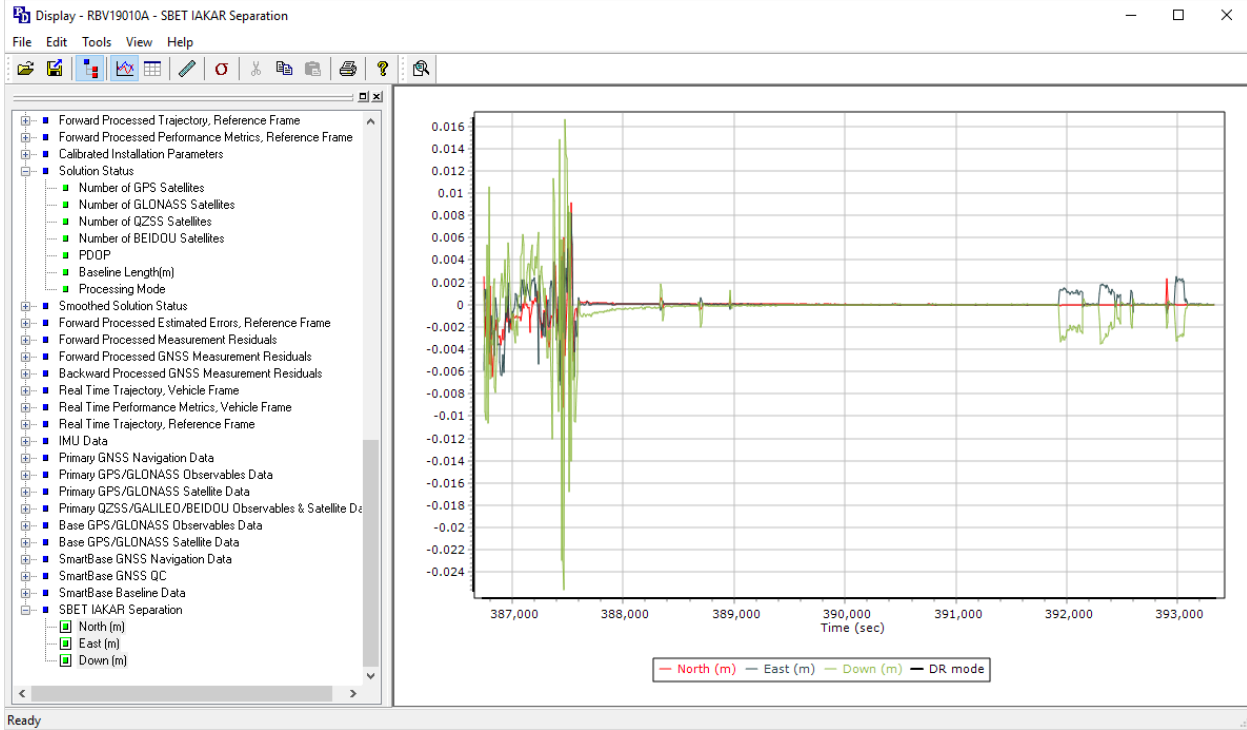
Timing
Start: 385100.000
End: 393330.000
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

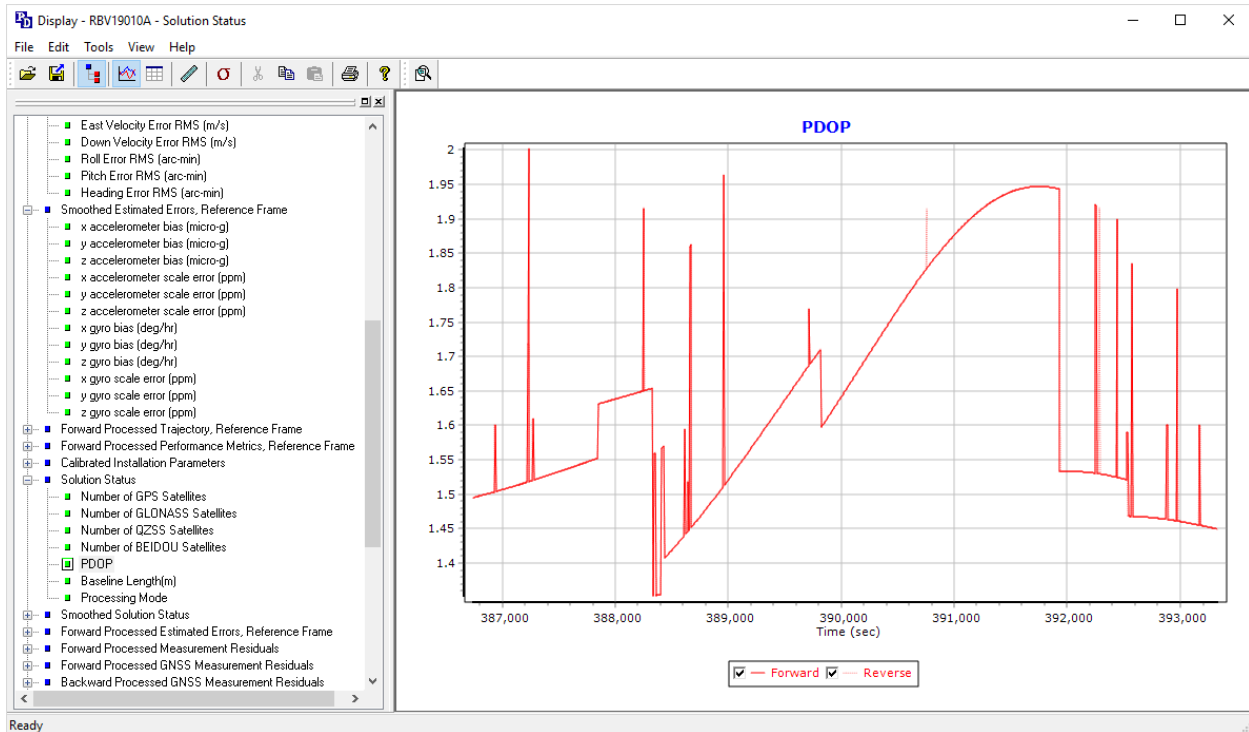
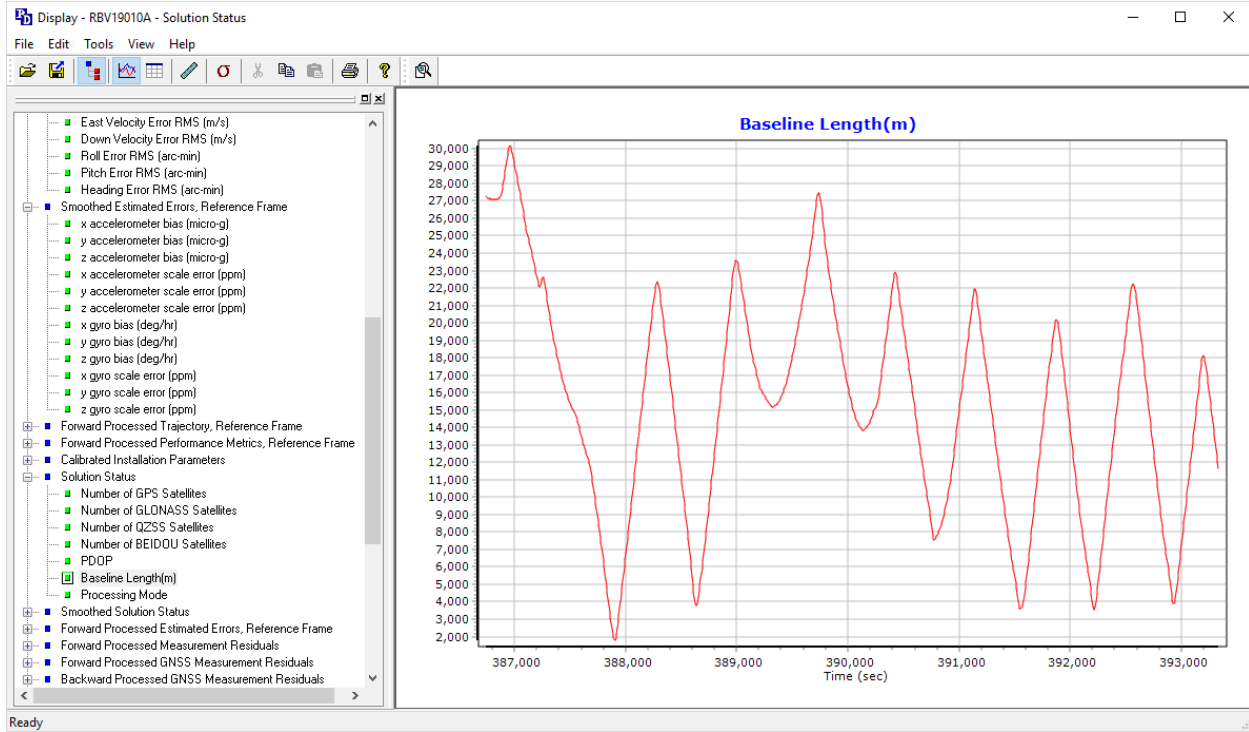
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

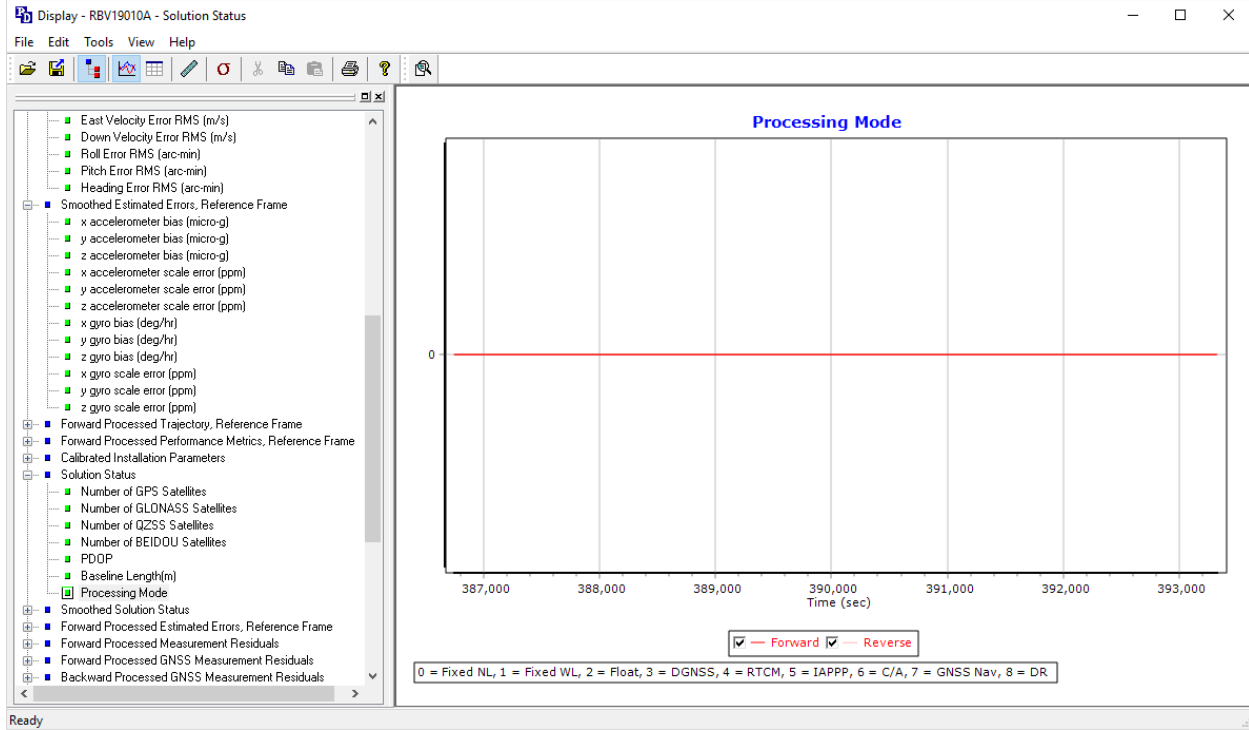
OK Cancel



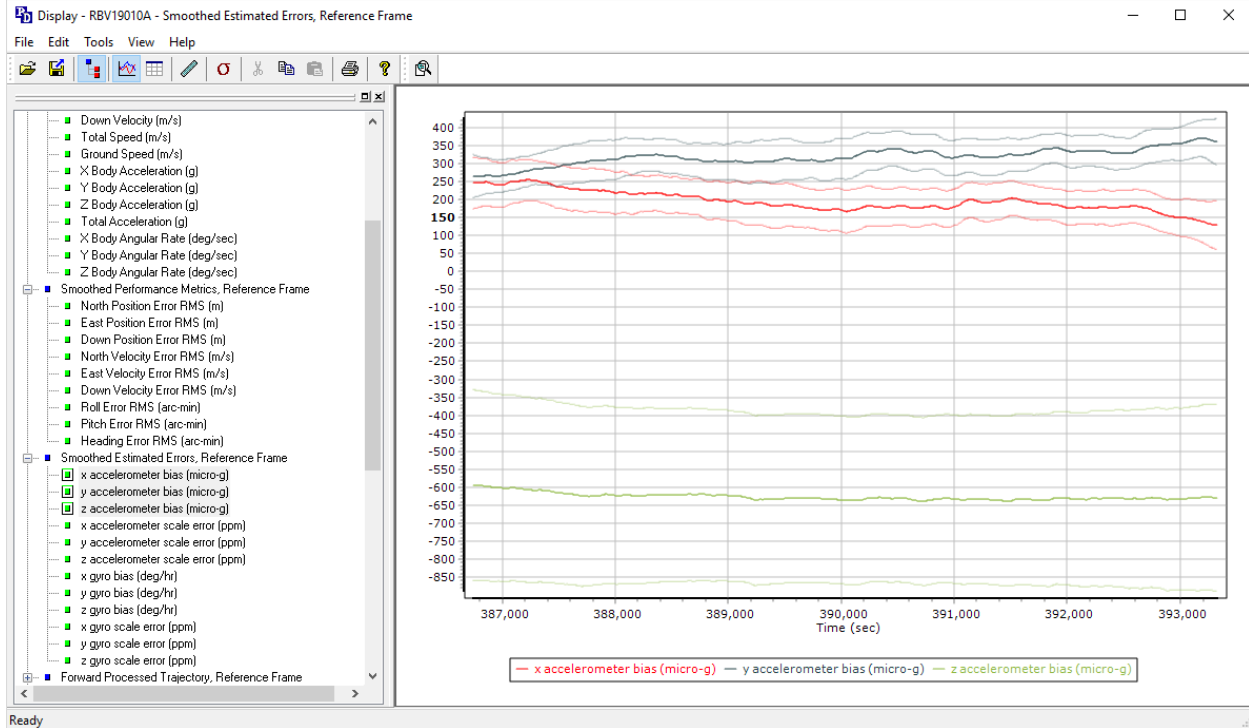


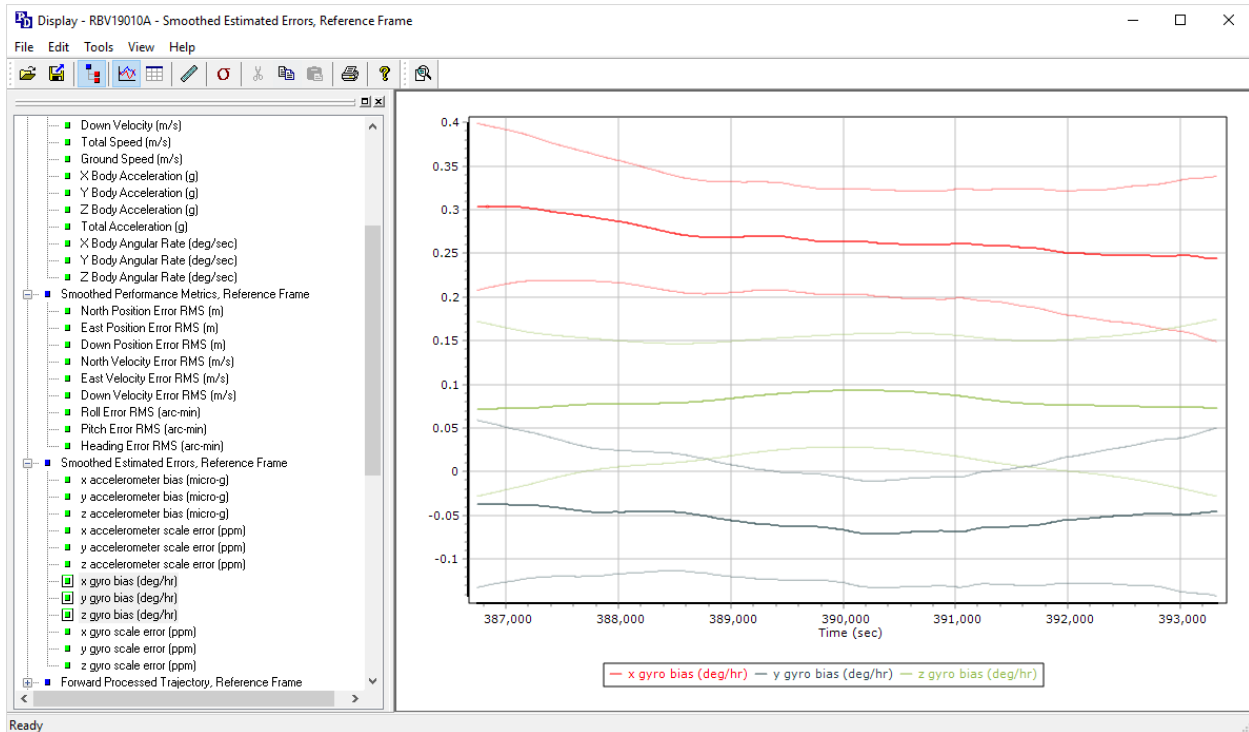
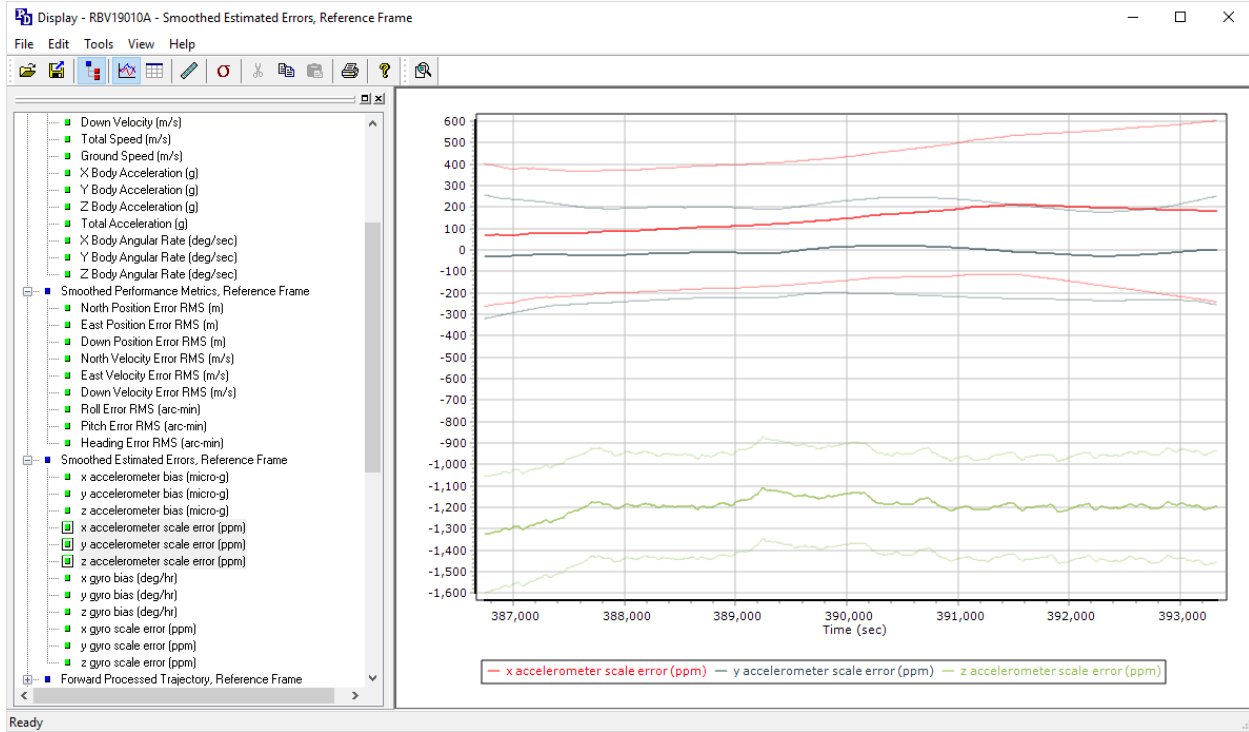


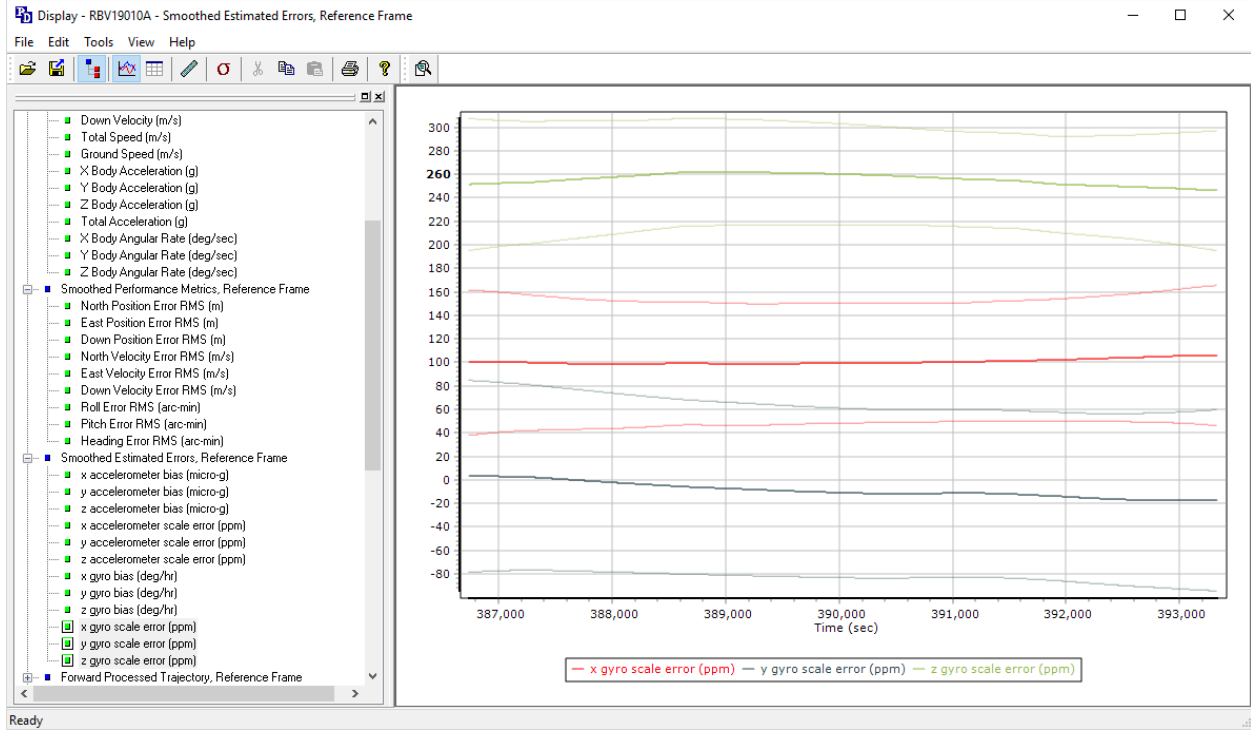




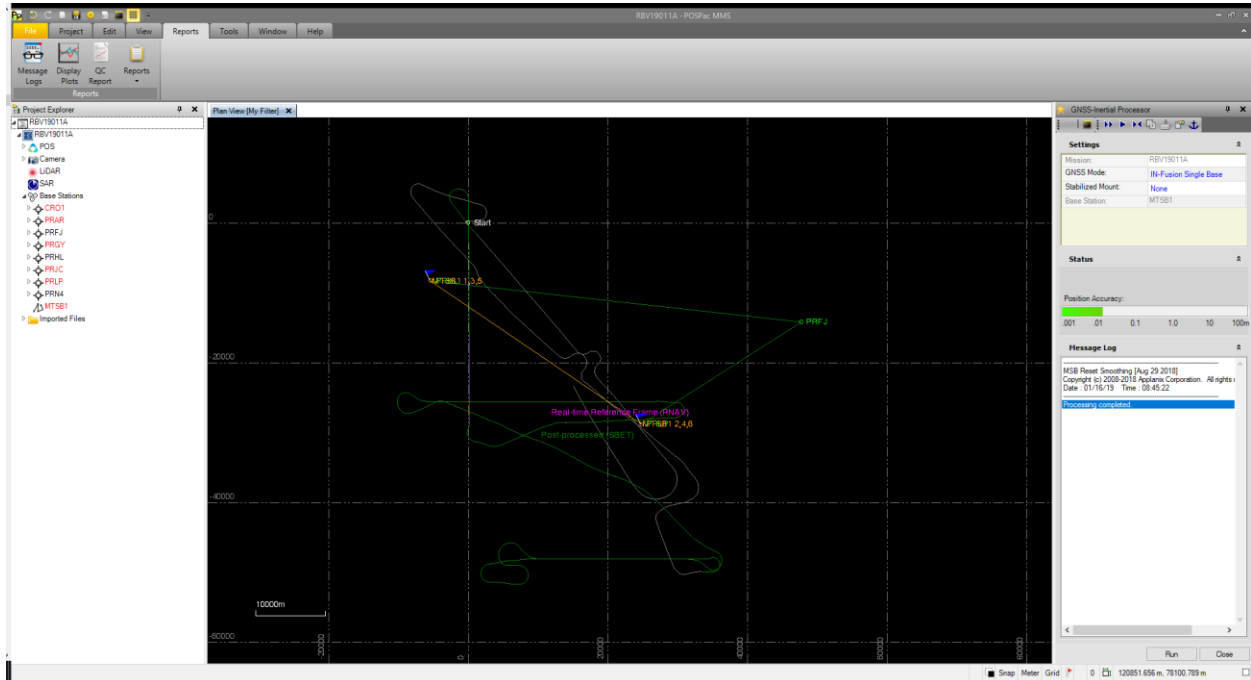
Sensor Errors

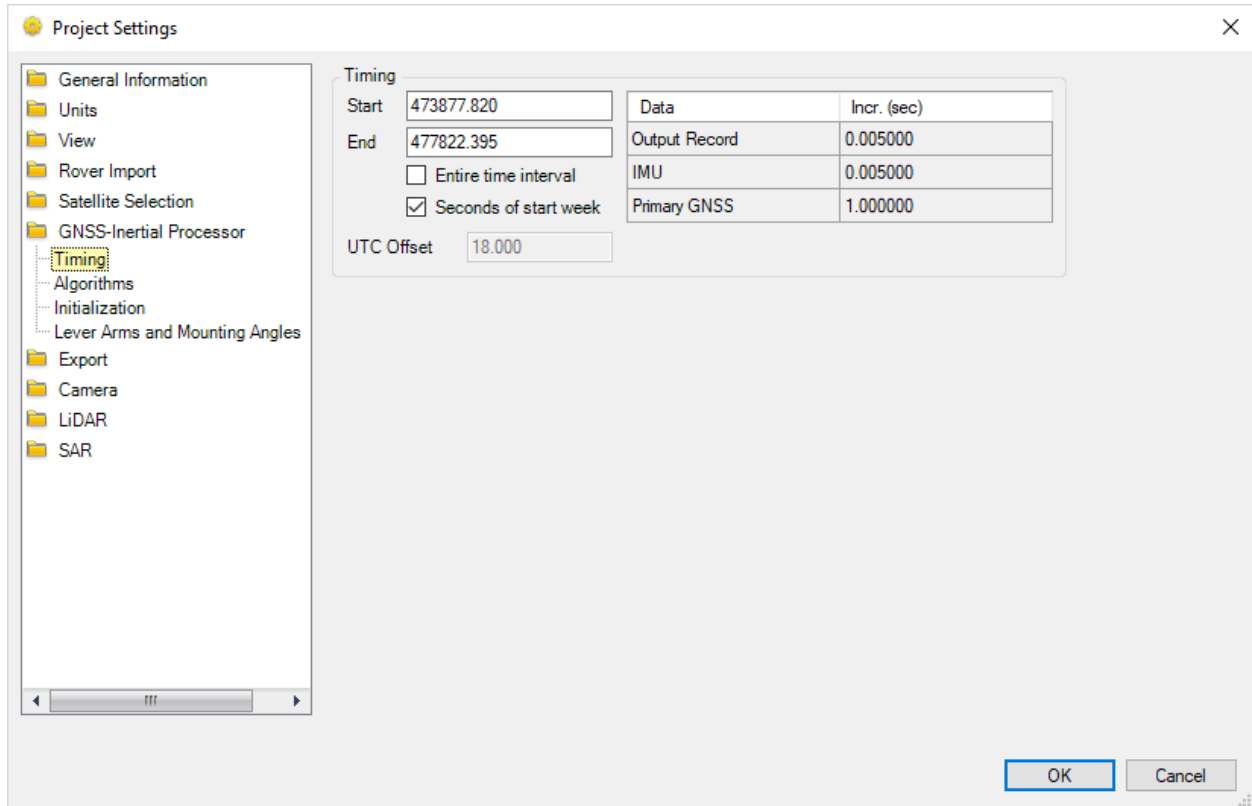
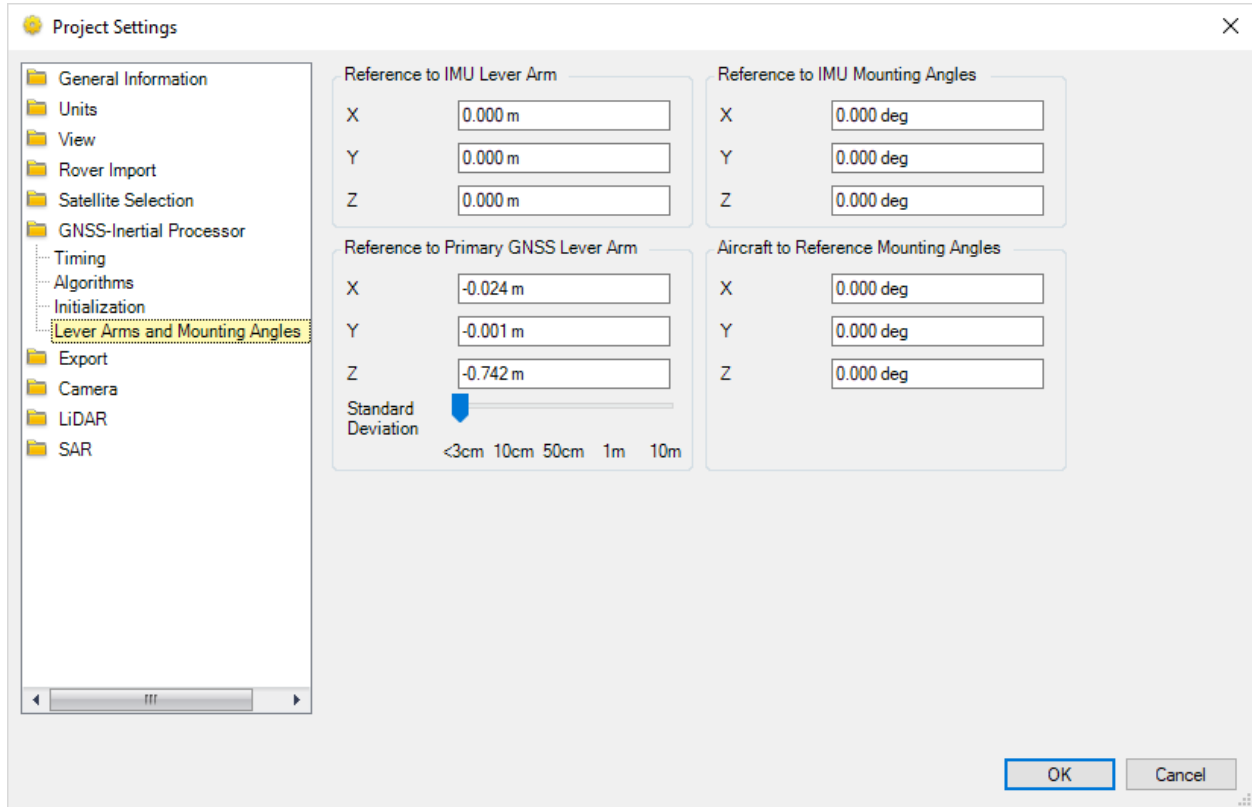


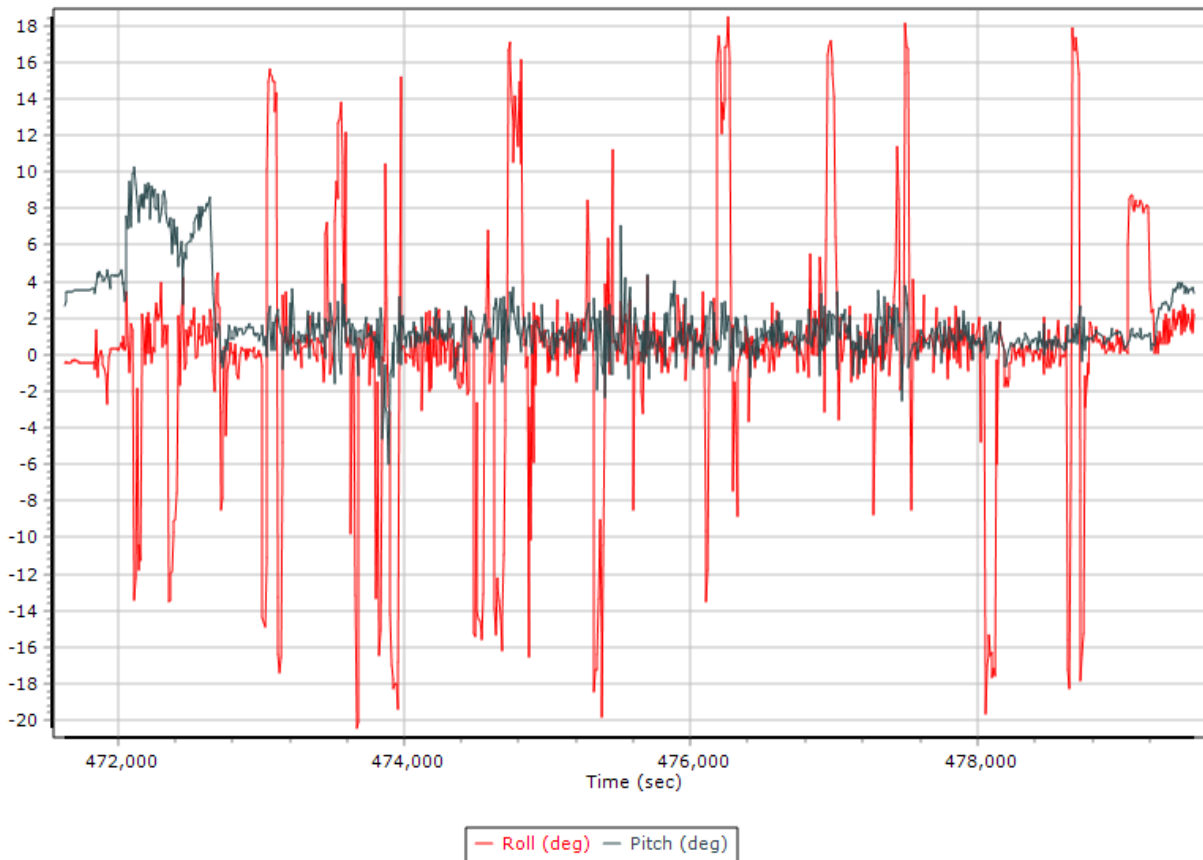
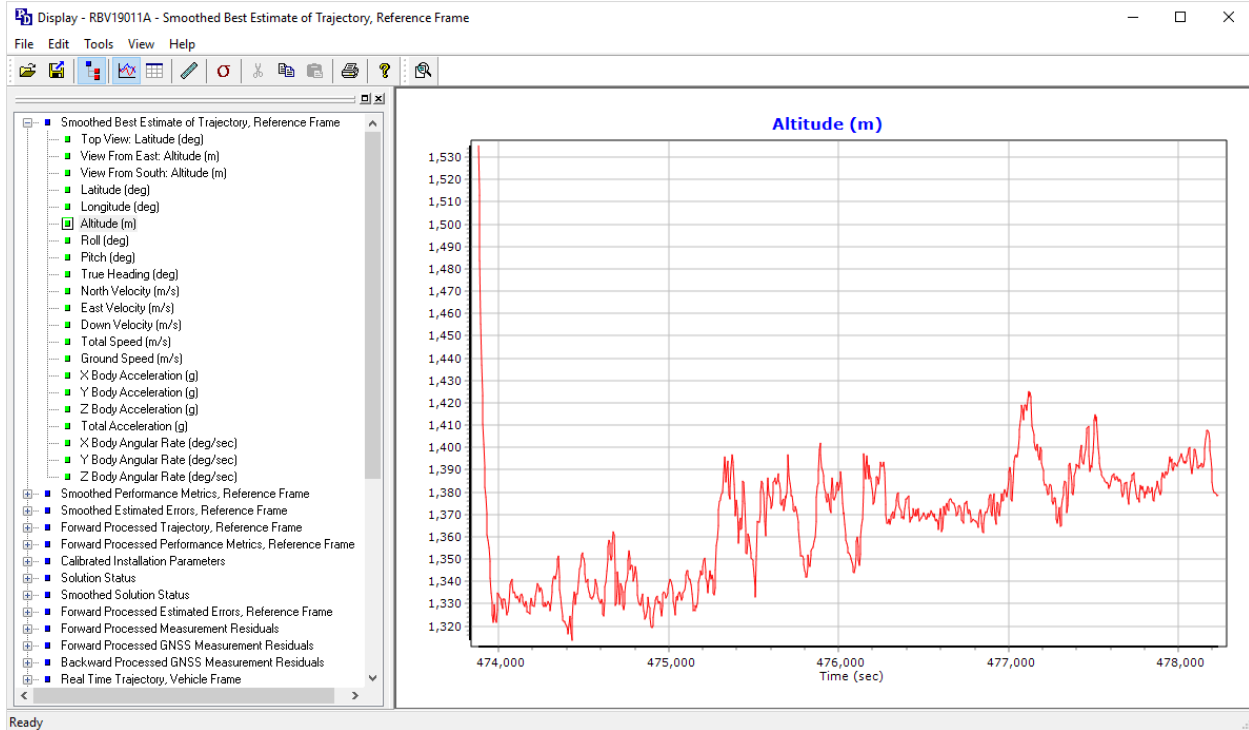


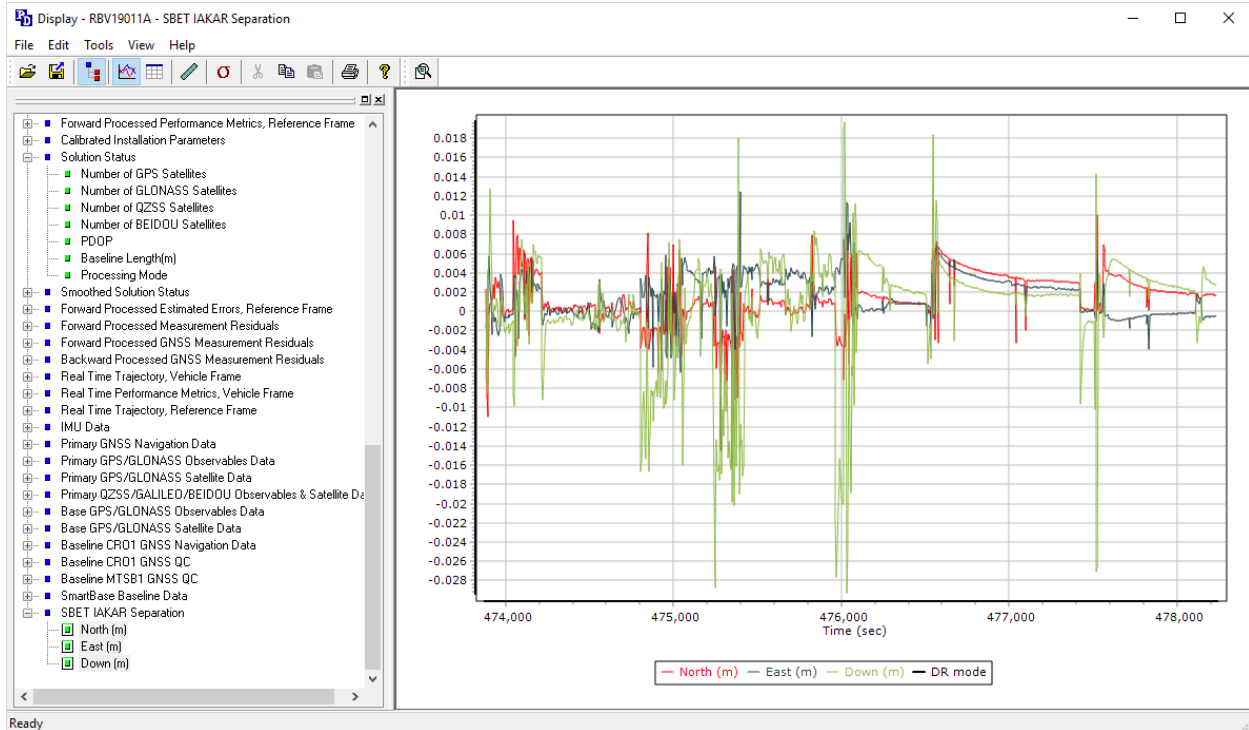
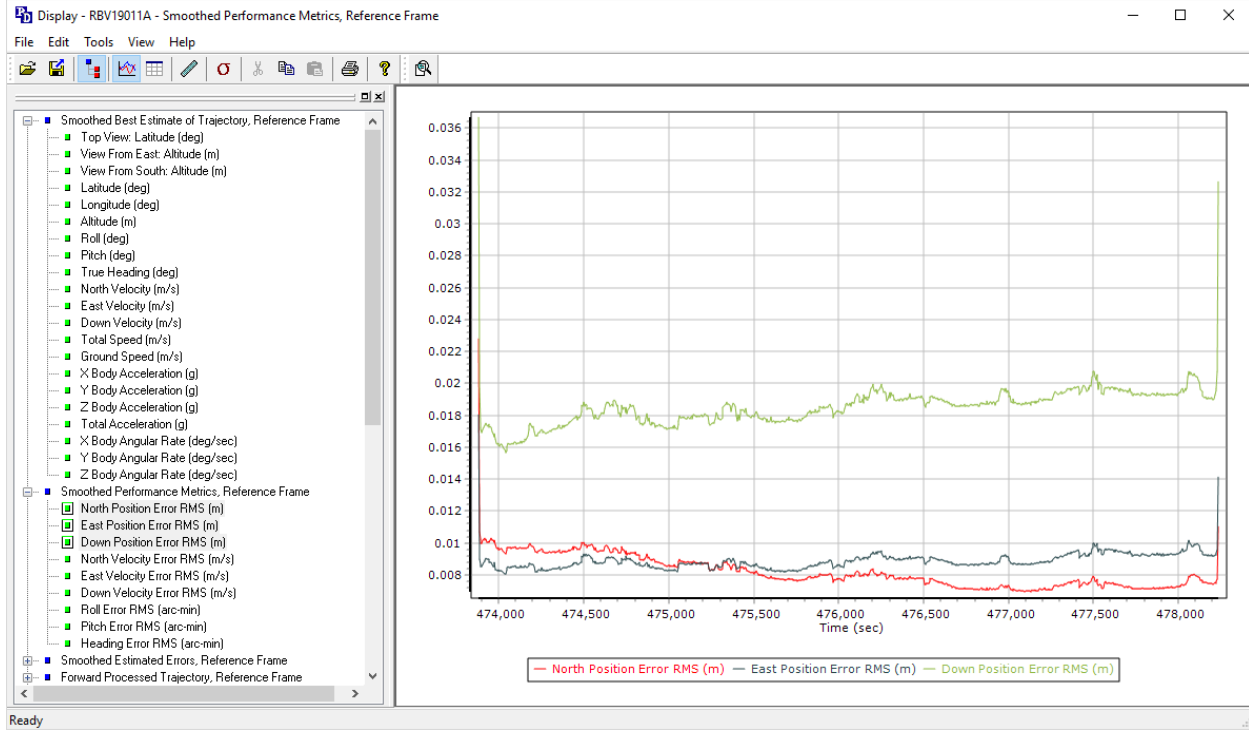


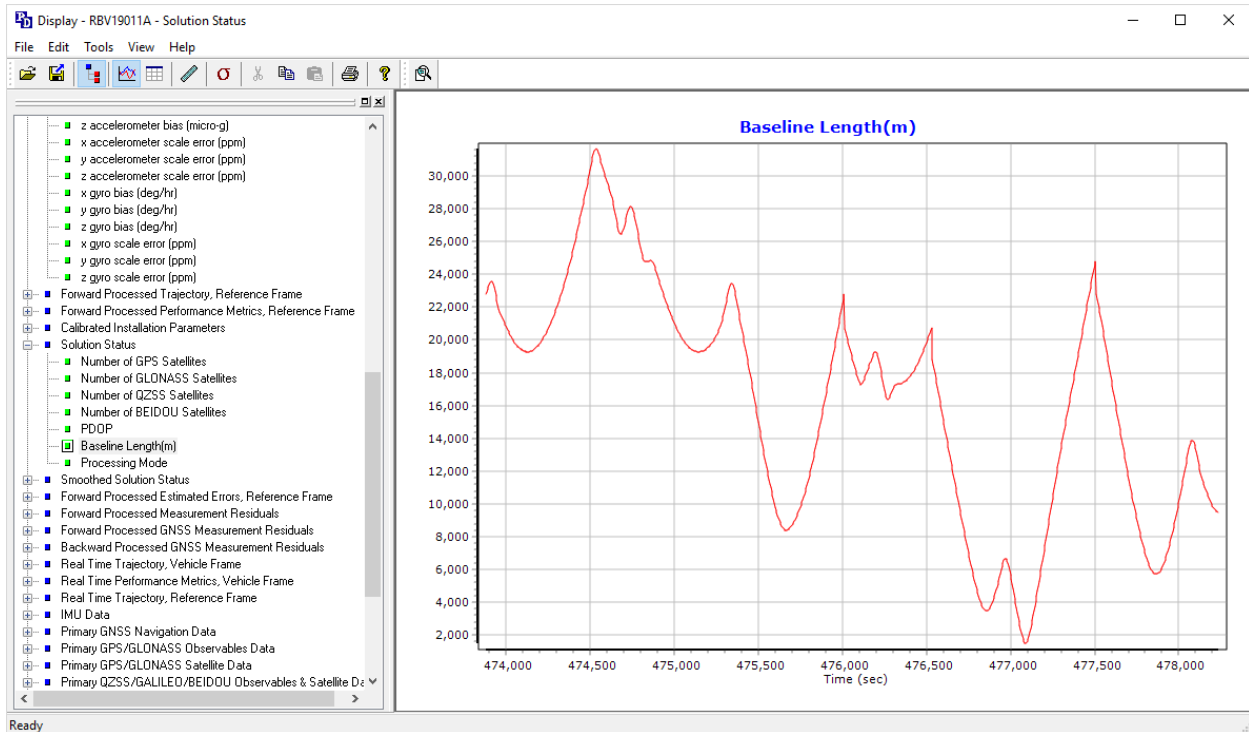
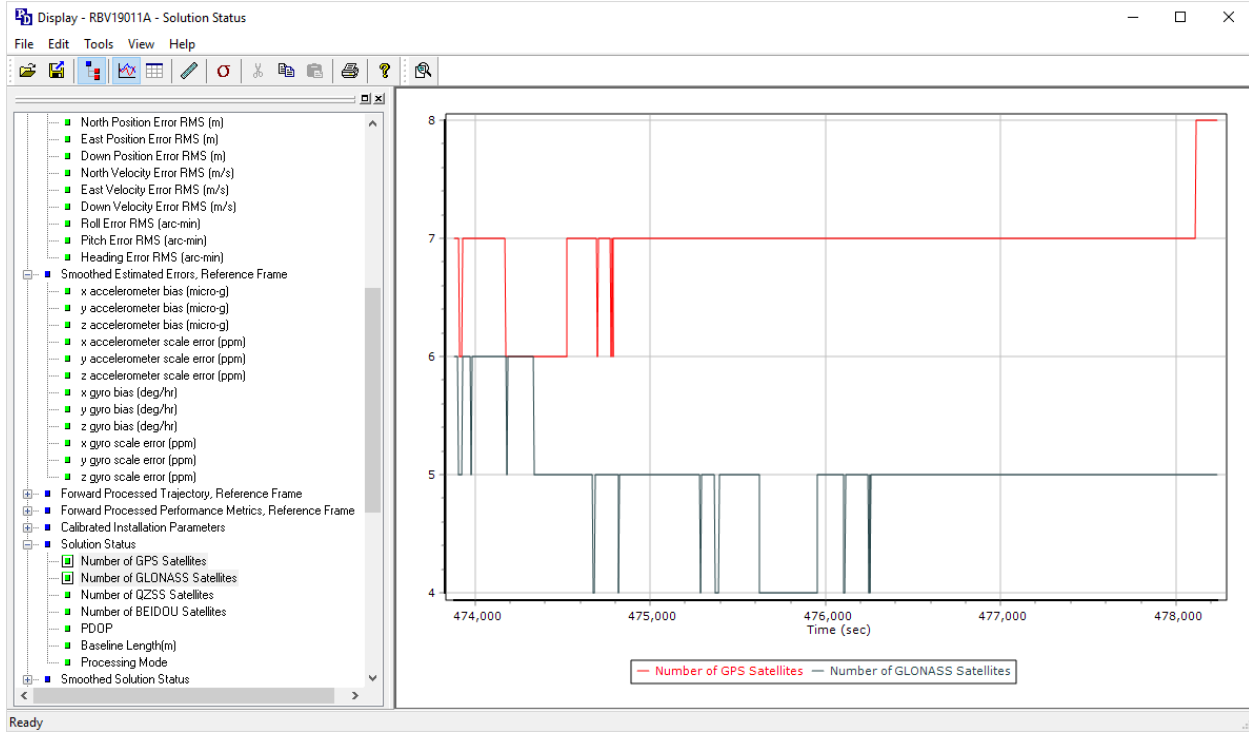
RBV19011A

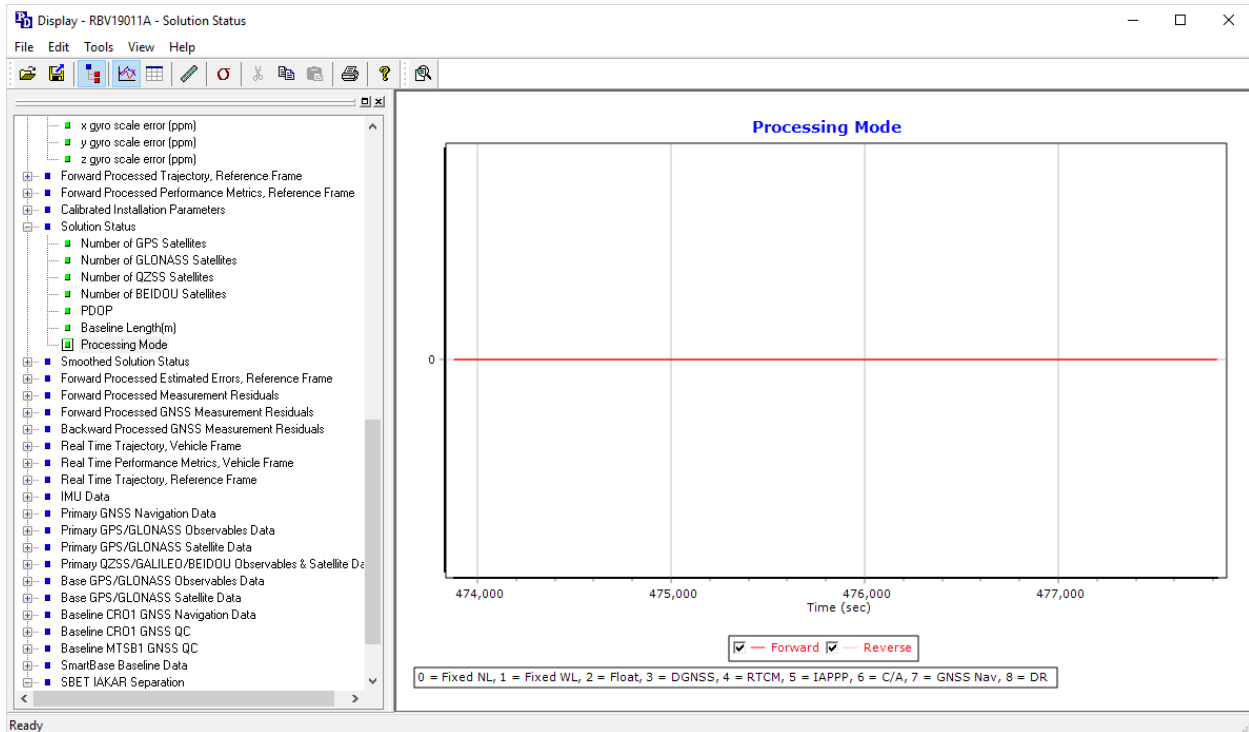
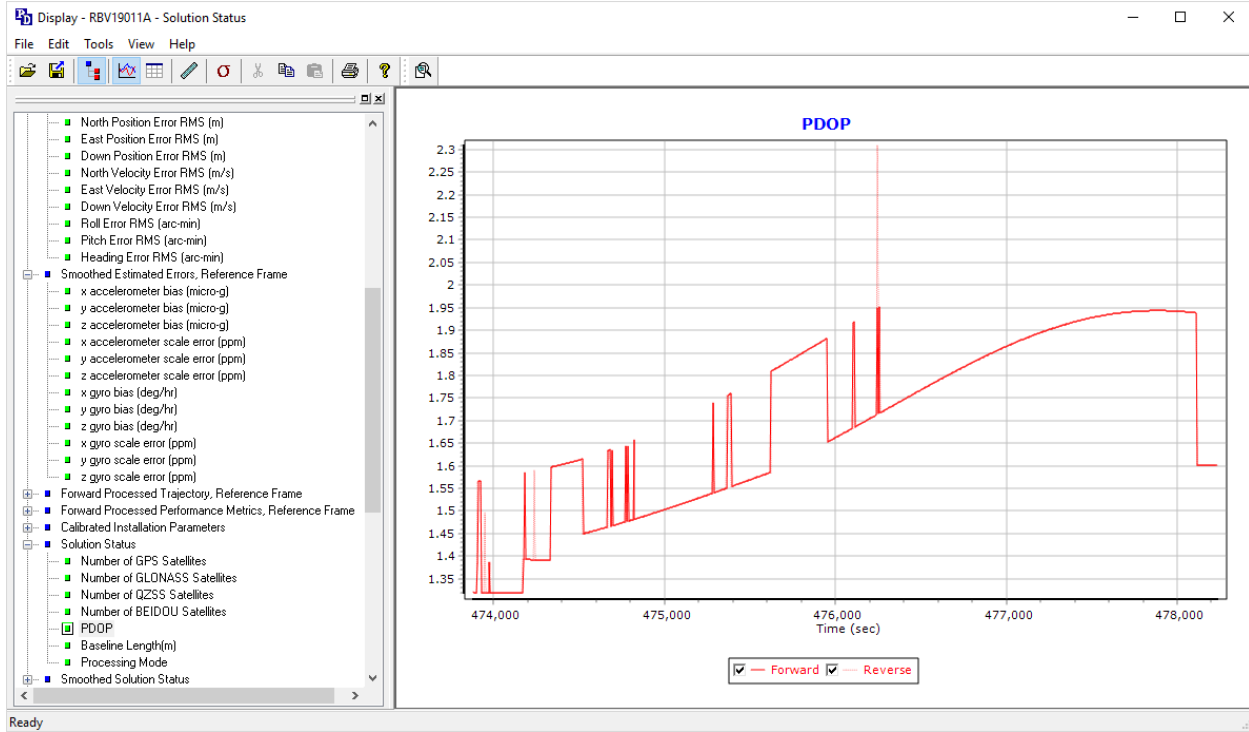




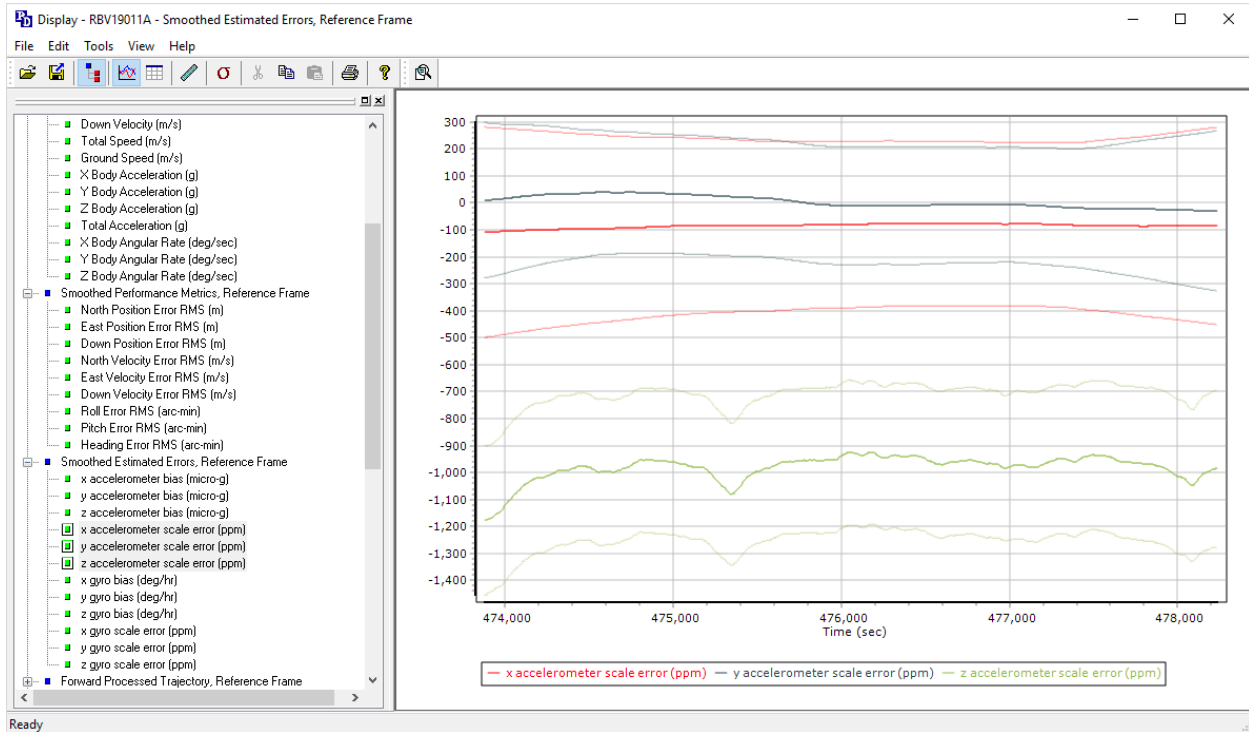
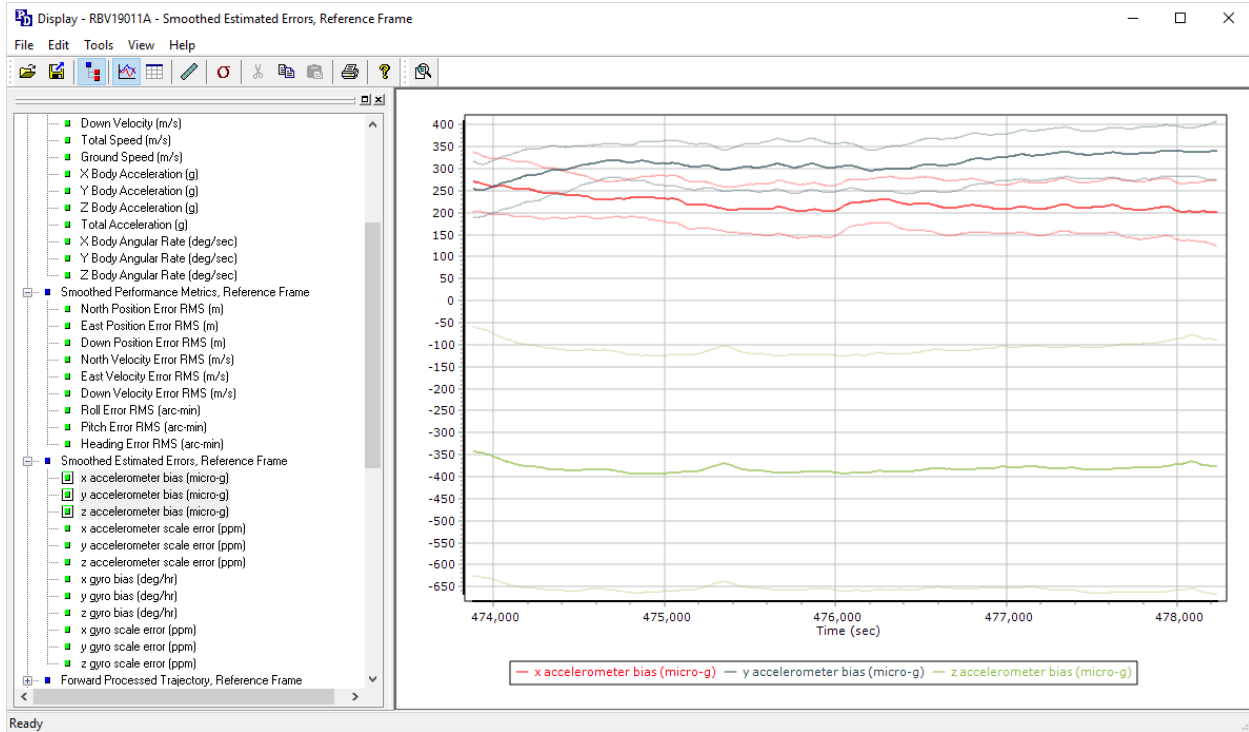


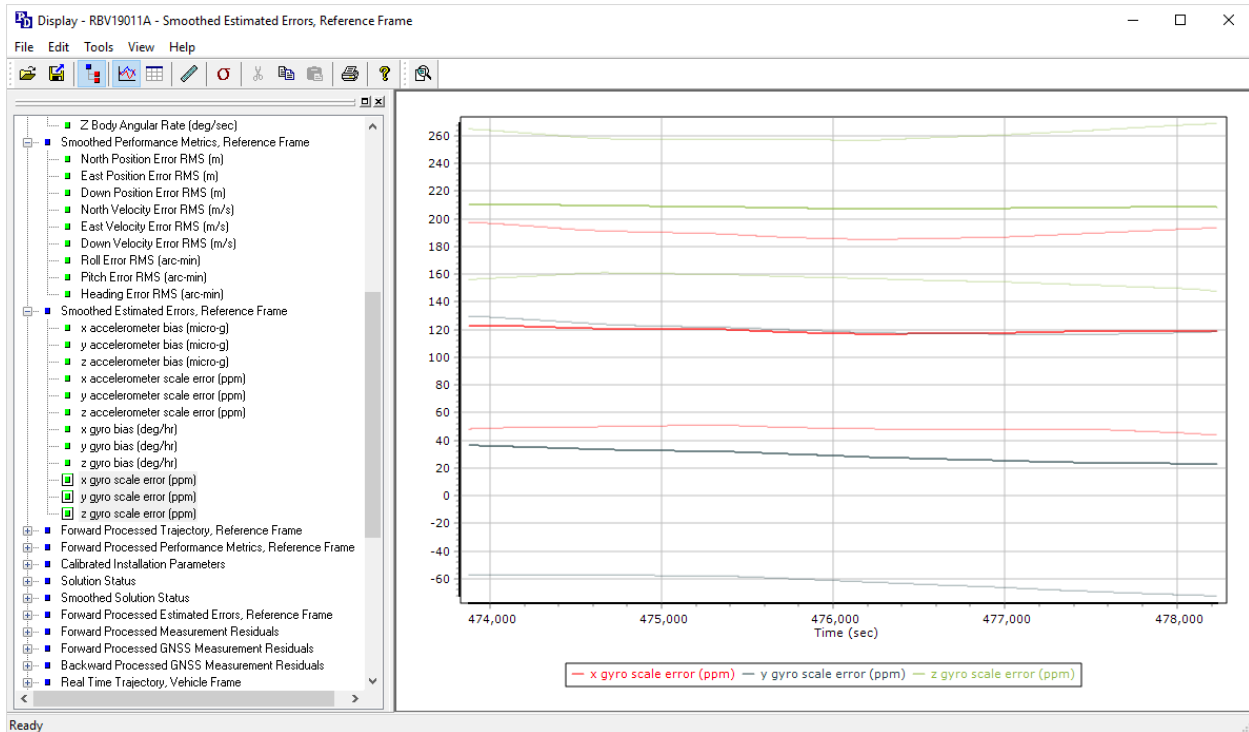
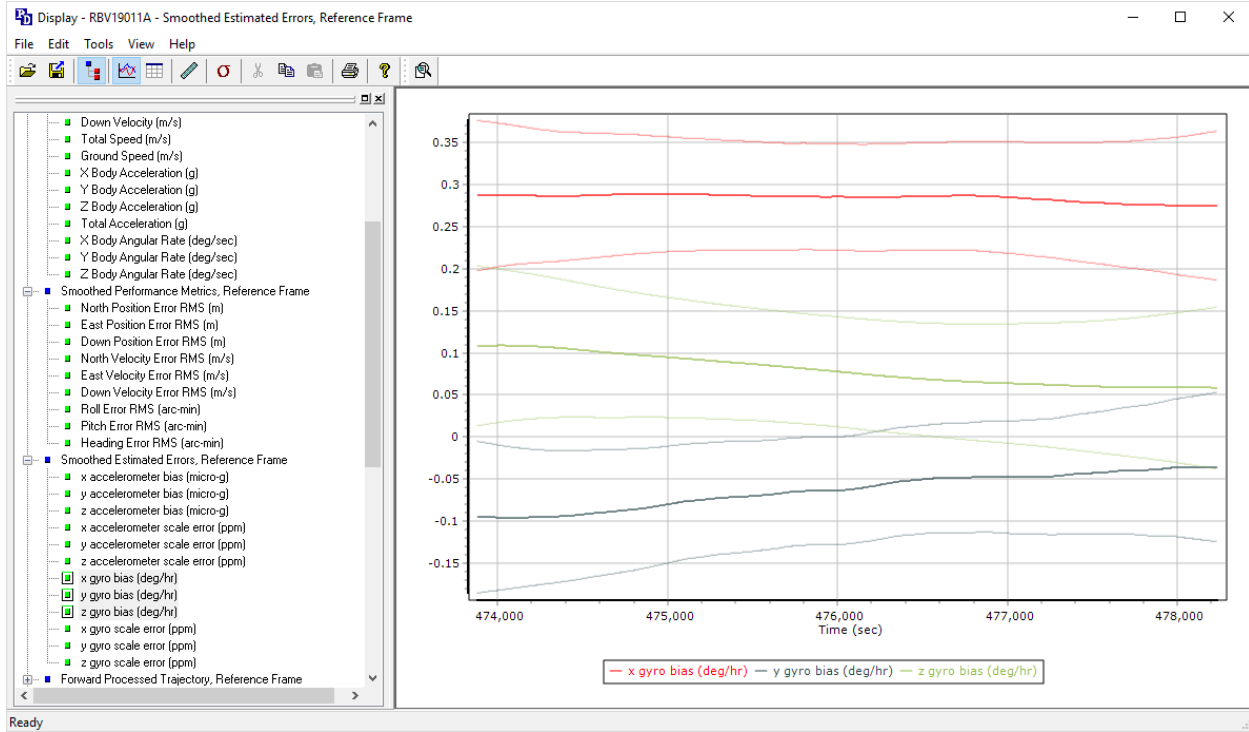




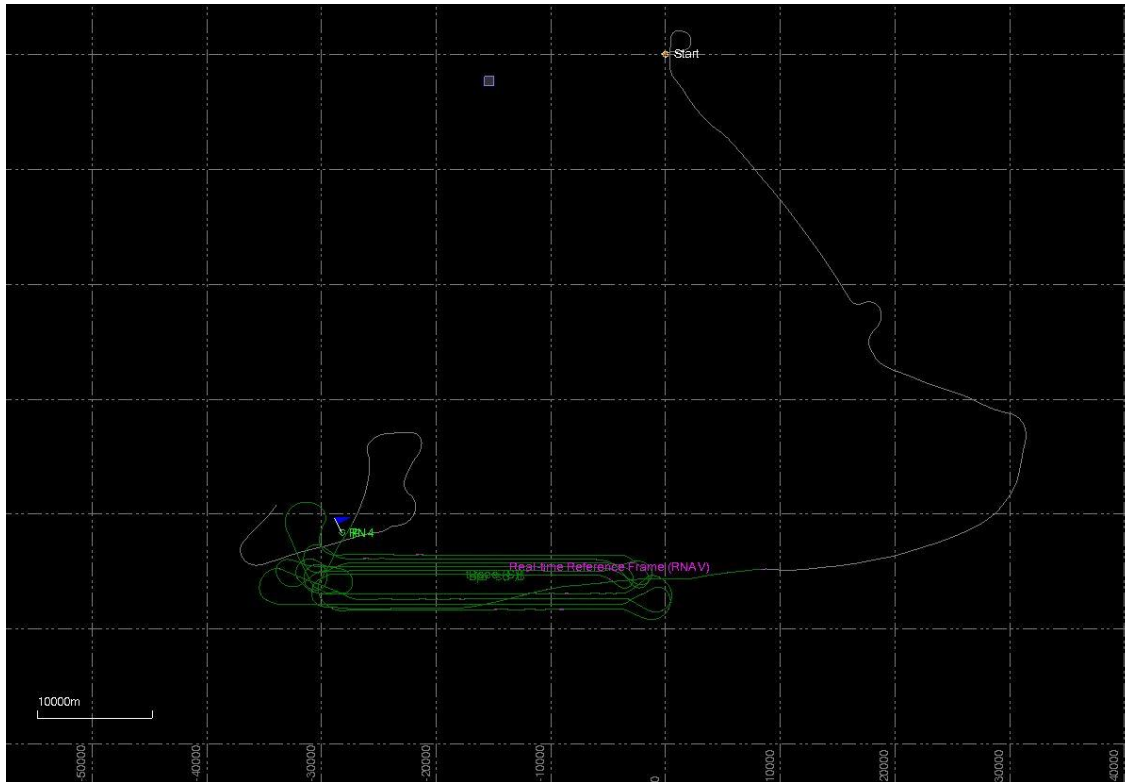


Sensor Errors





RBV19114A



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: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 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

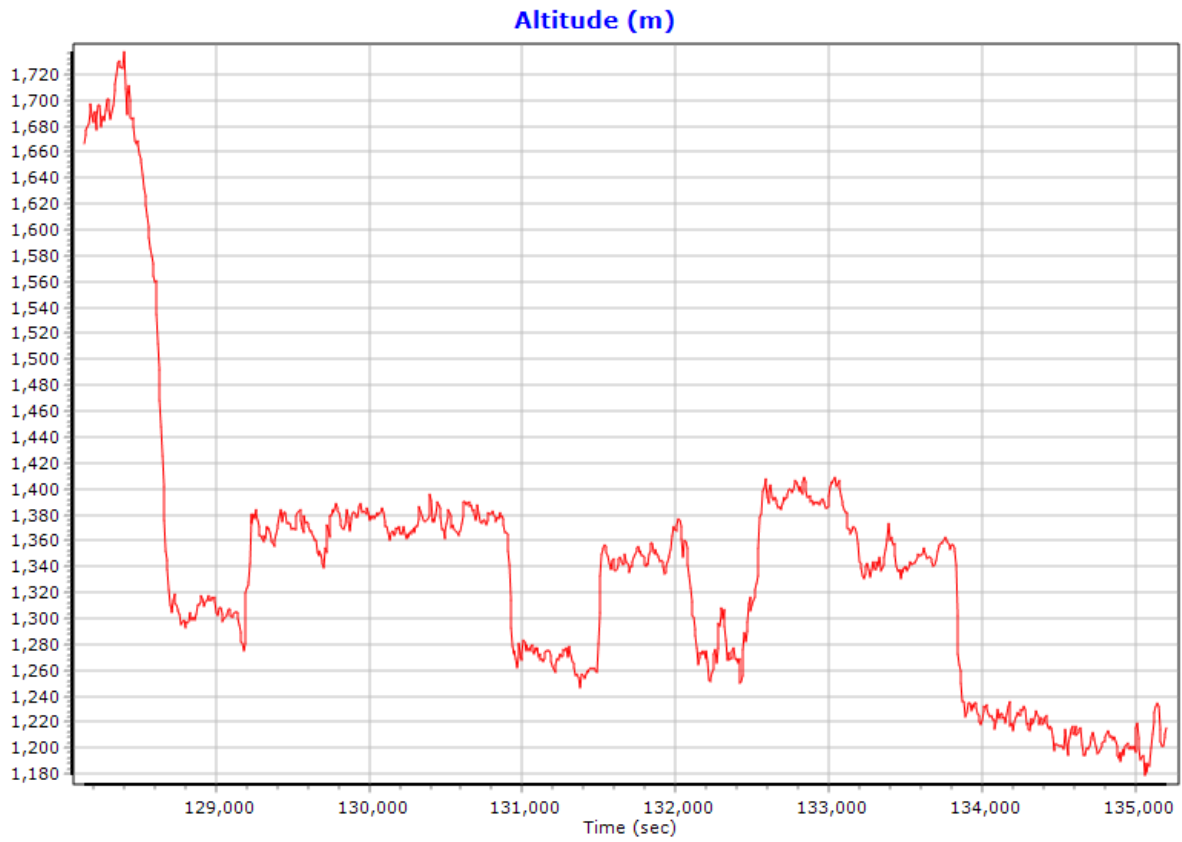
Timing

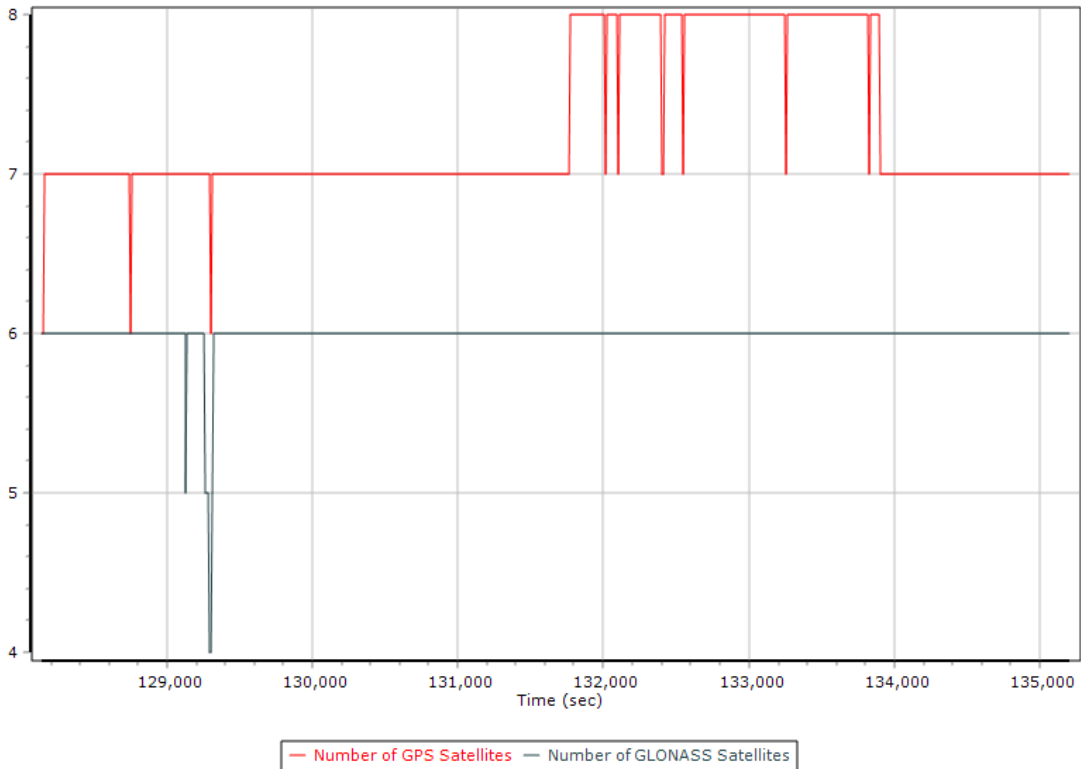
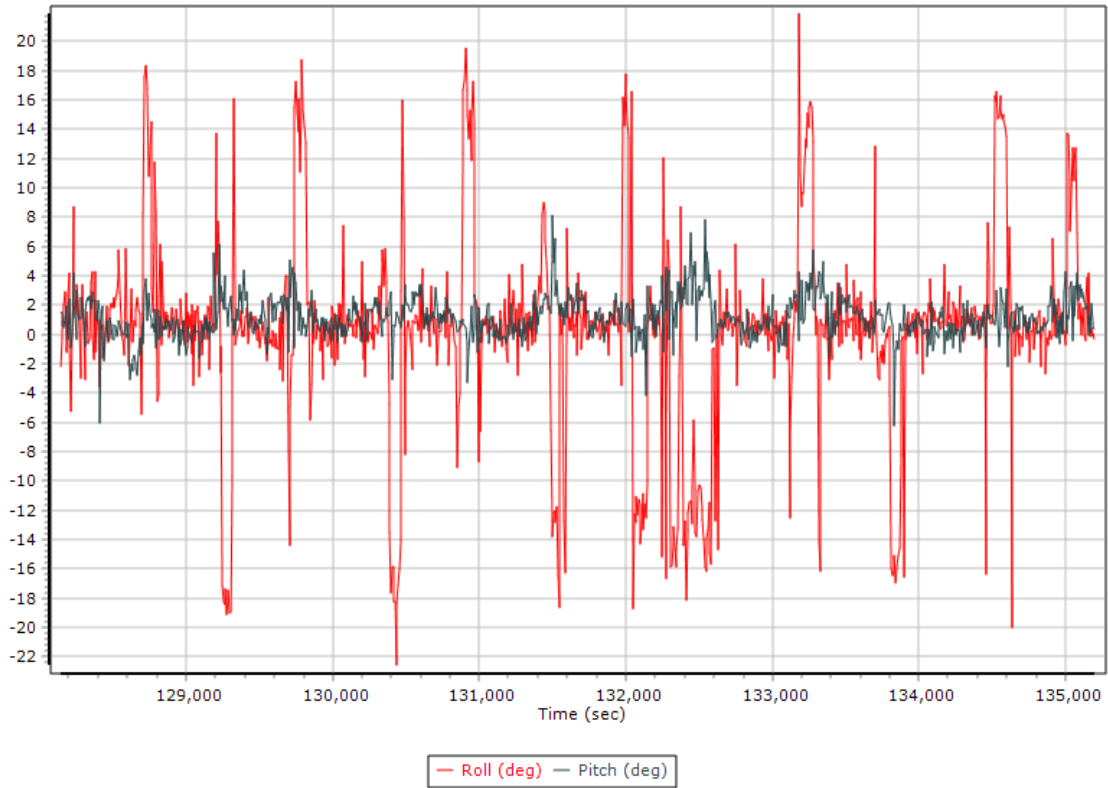
Start: 128140.236
End: 135201.478

Entire time interval
 Seconds of start week

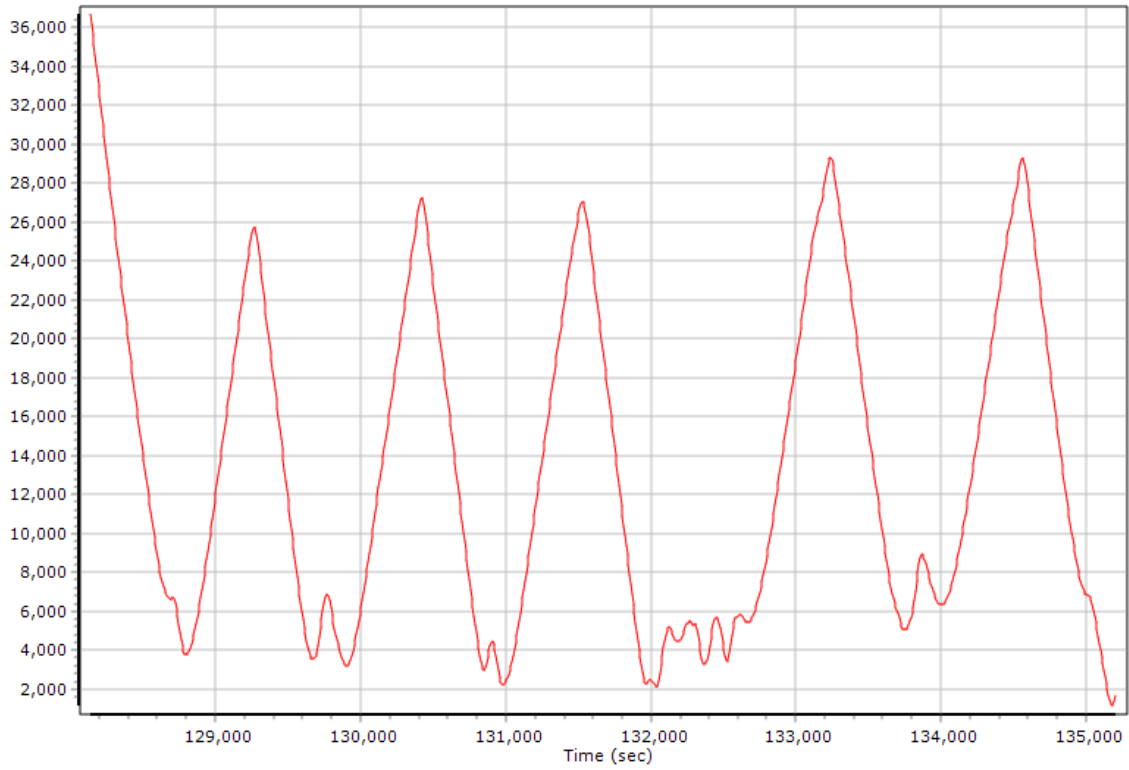
UTC Offset: 18.000

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

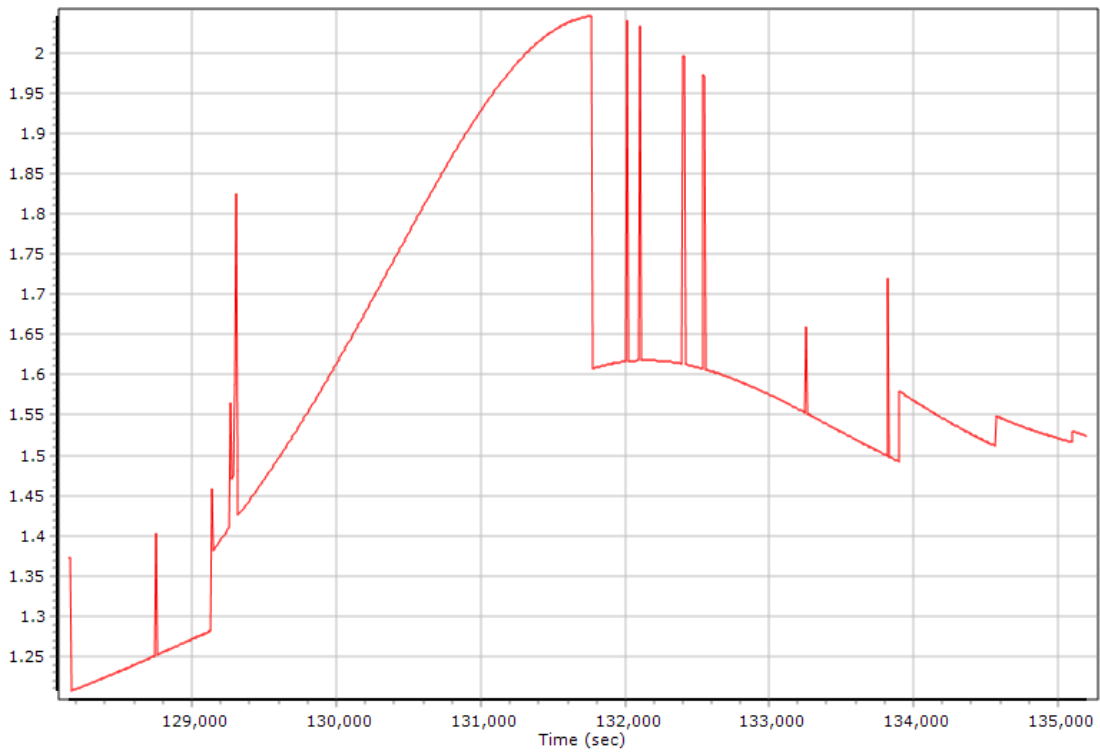




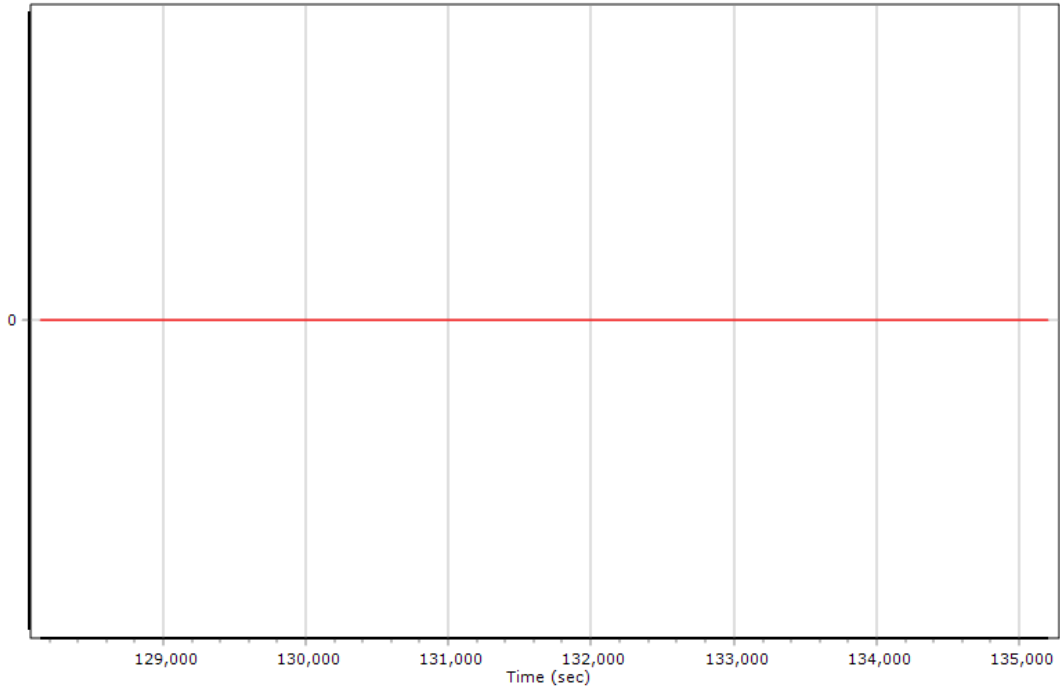
Baseline Length(m)



PDOP

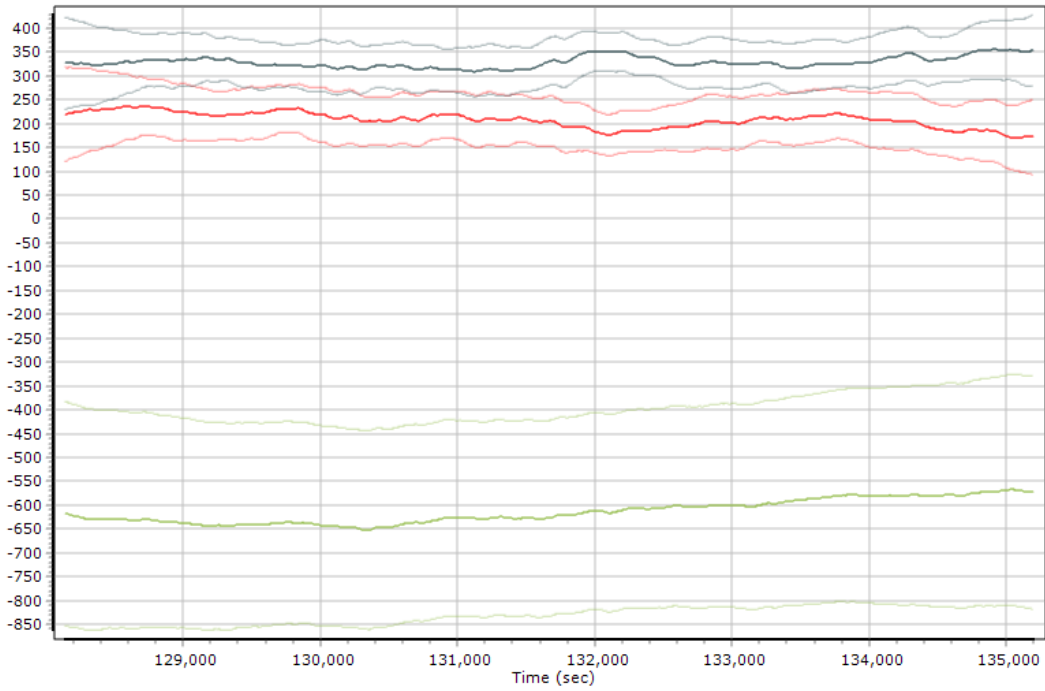


Processing Mode

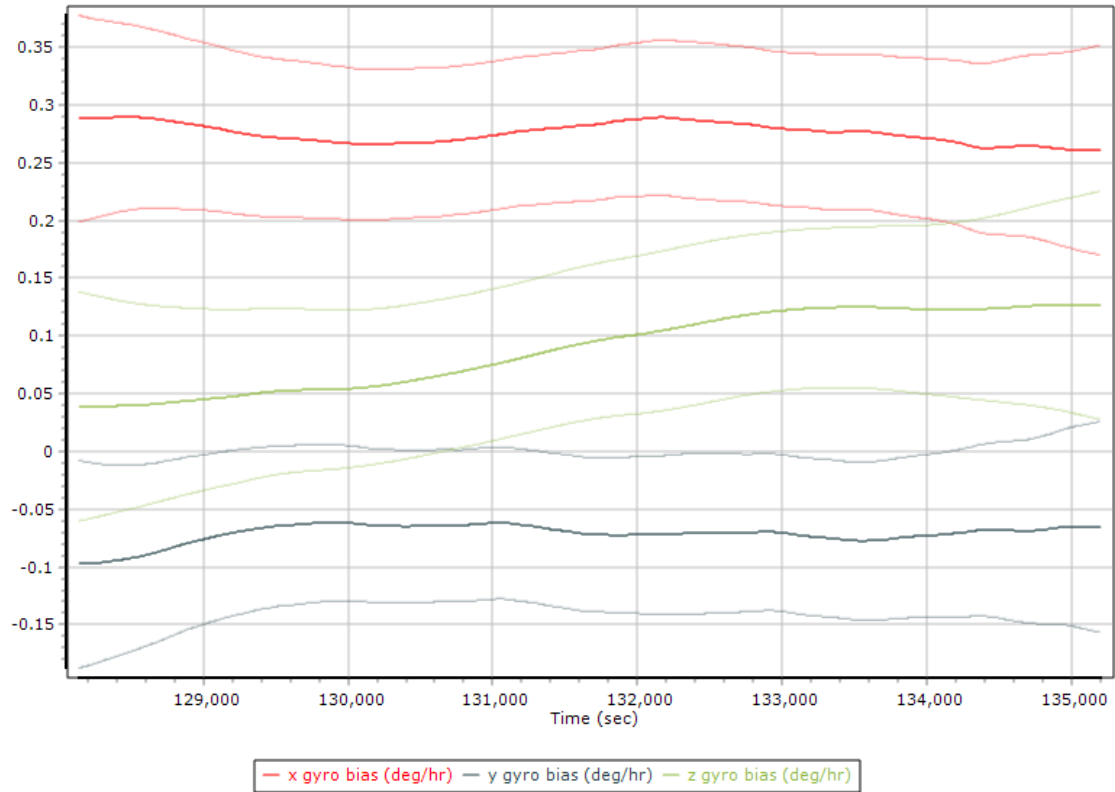
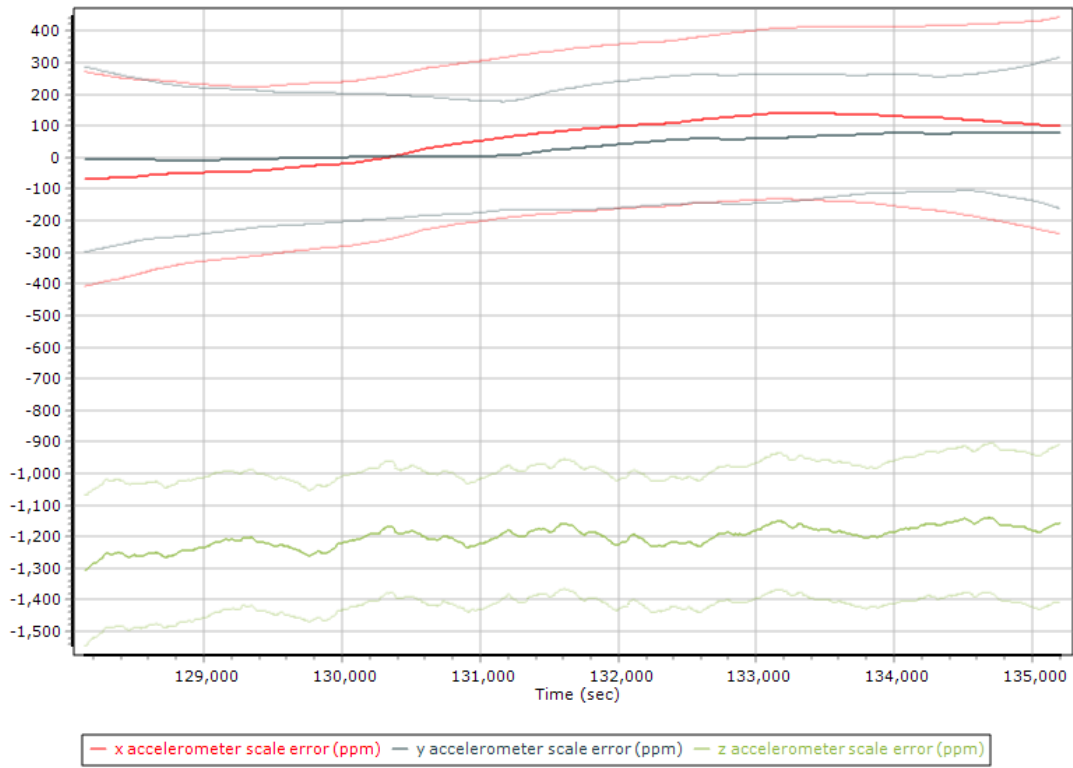


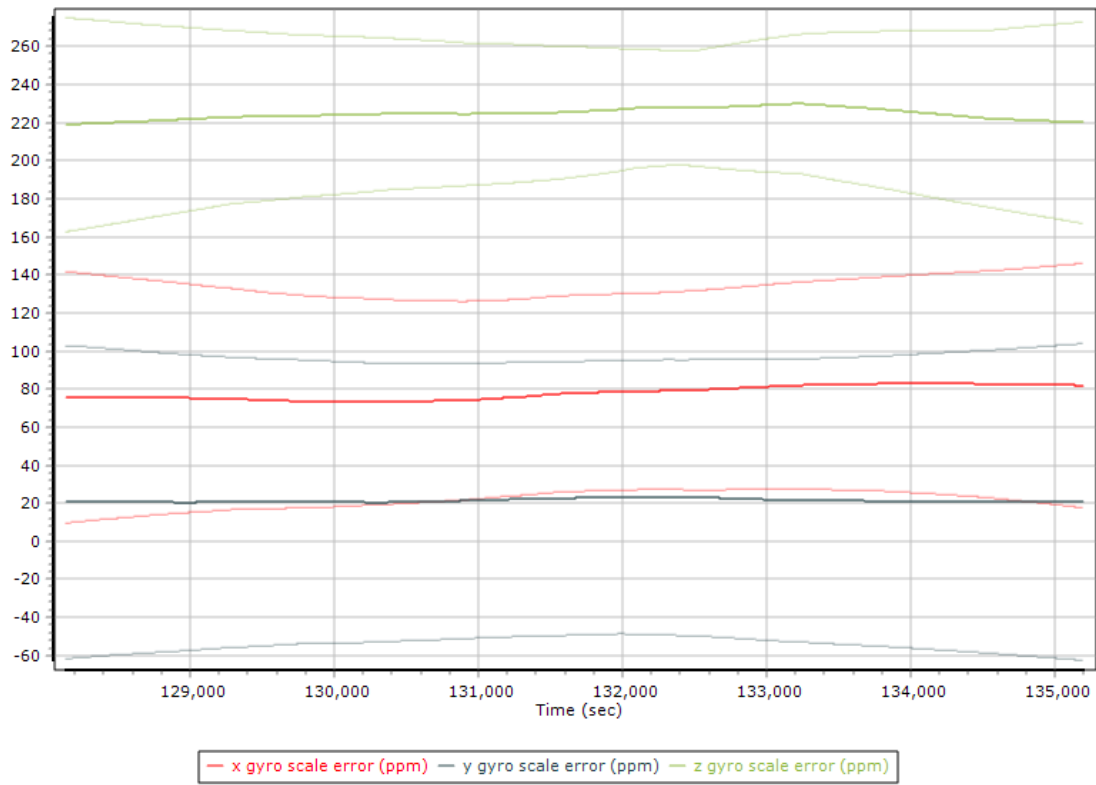
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

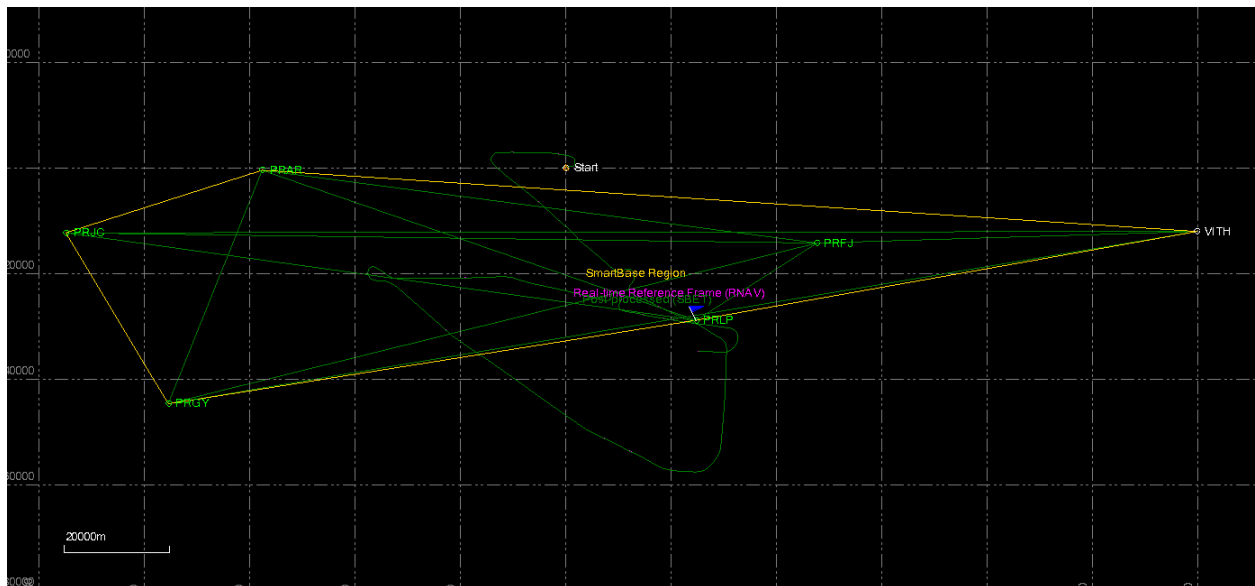


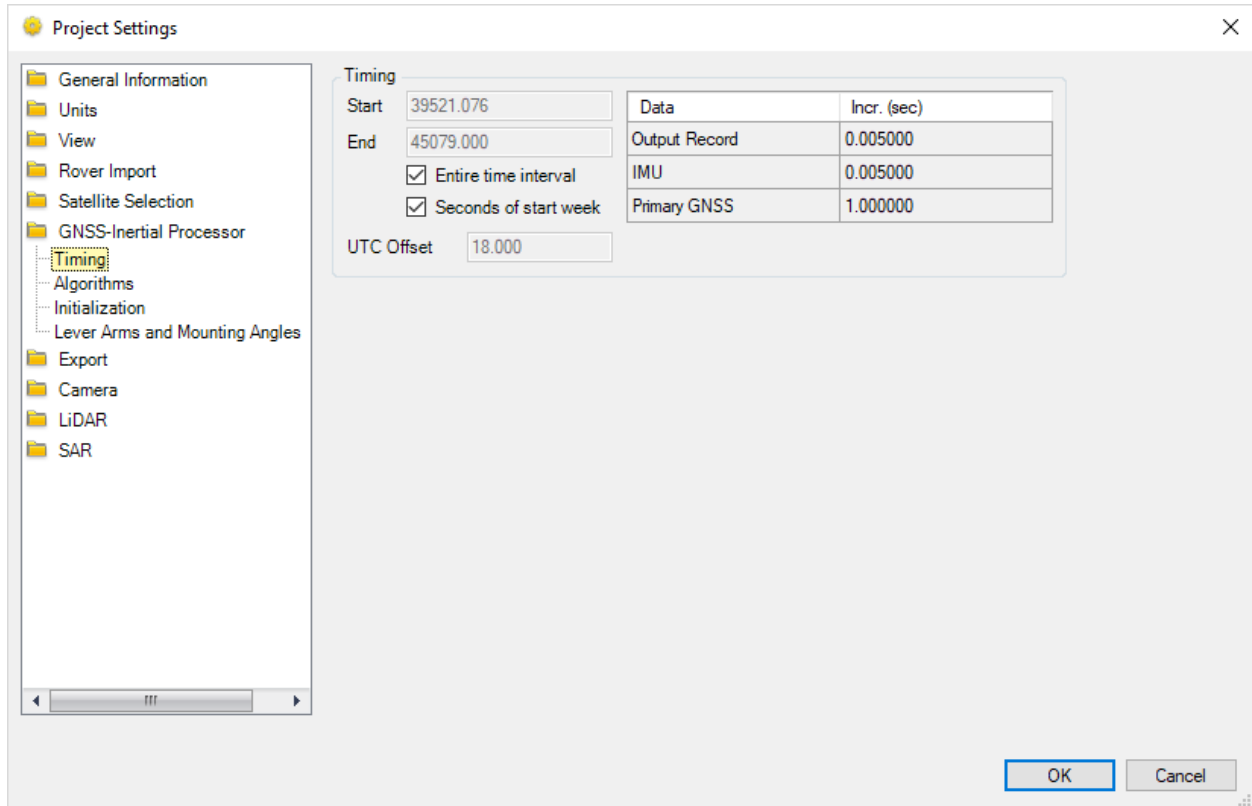
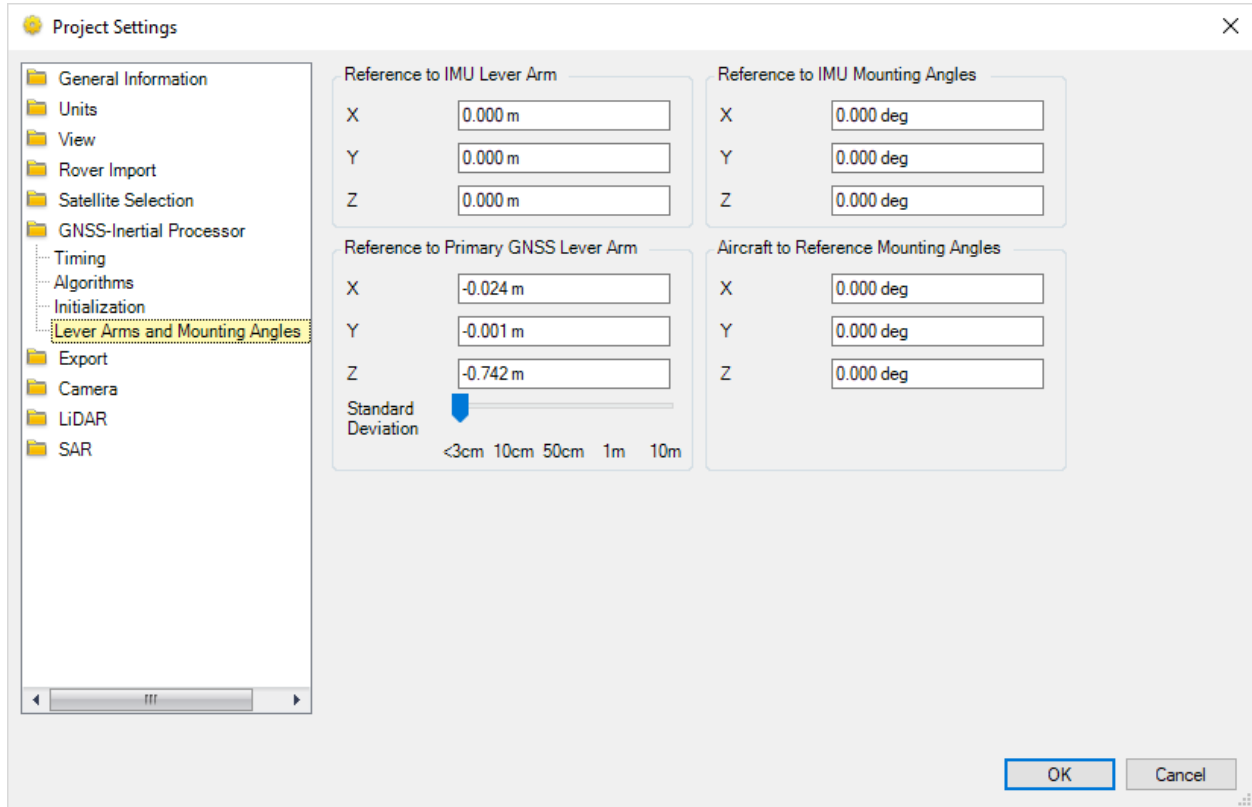
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)

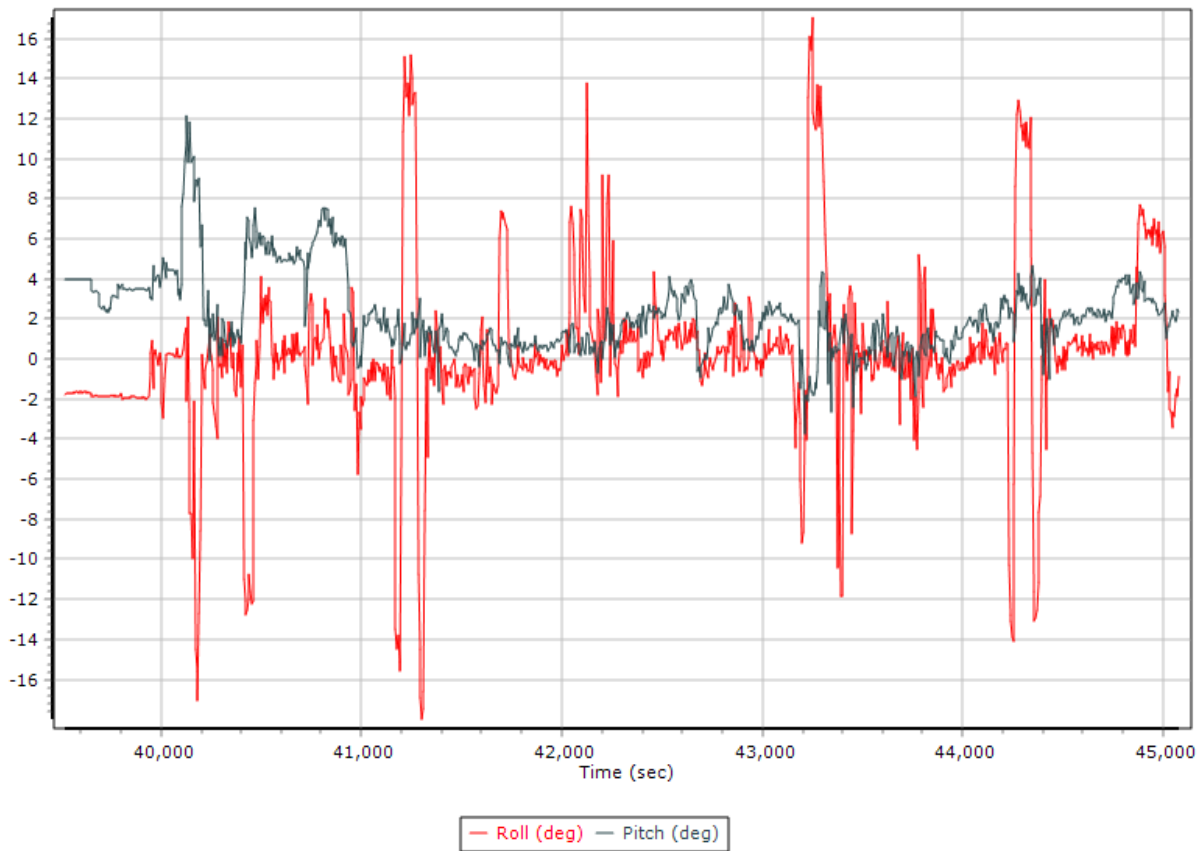
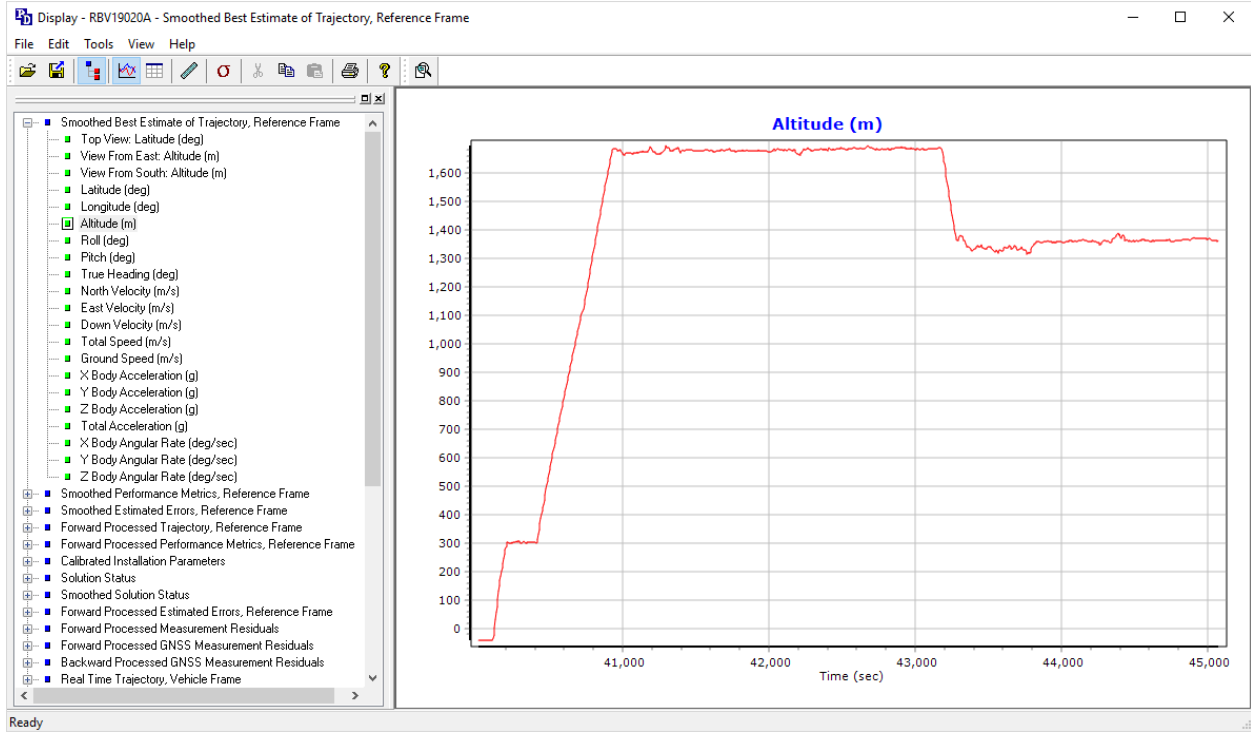


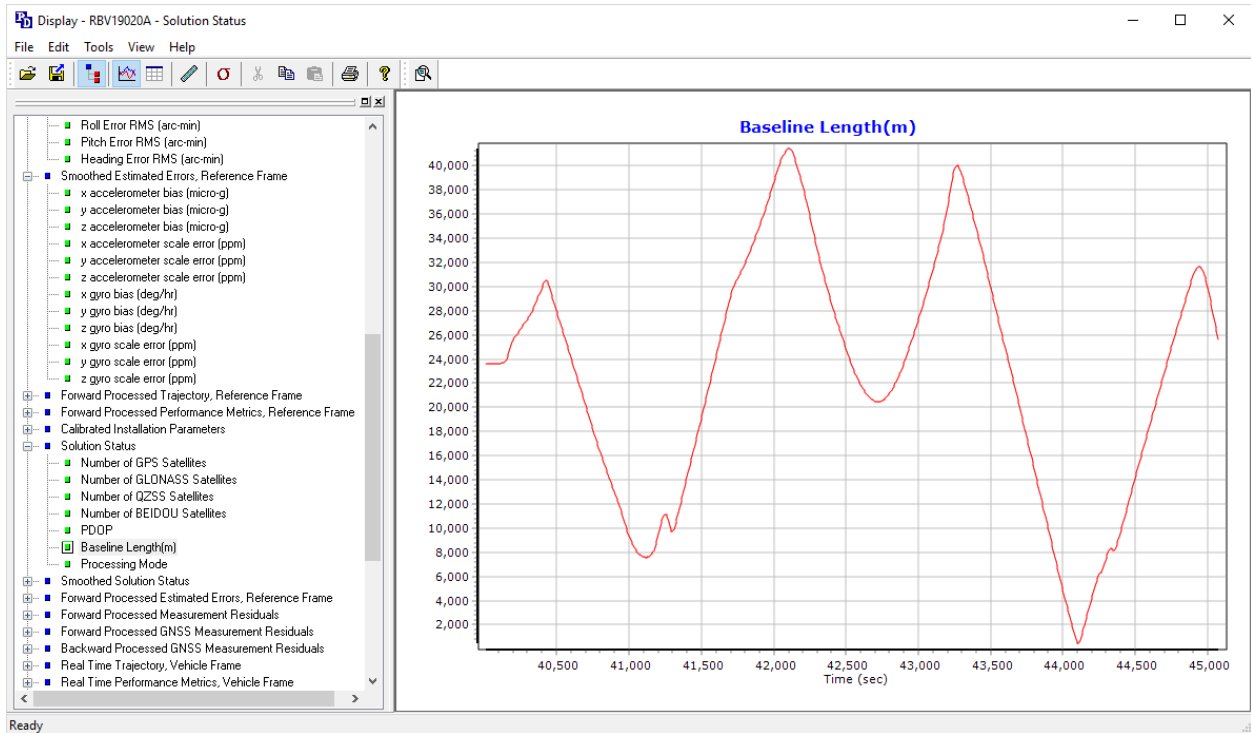
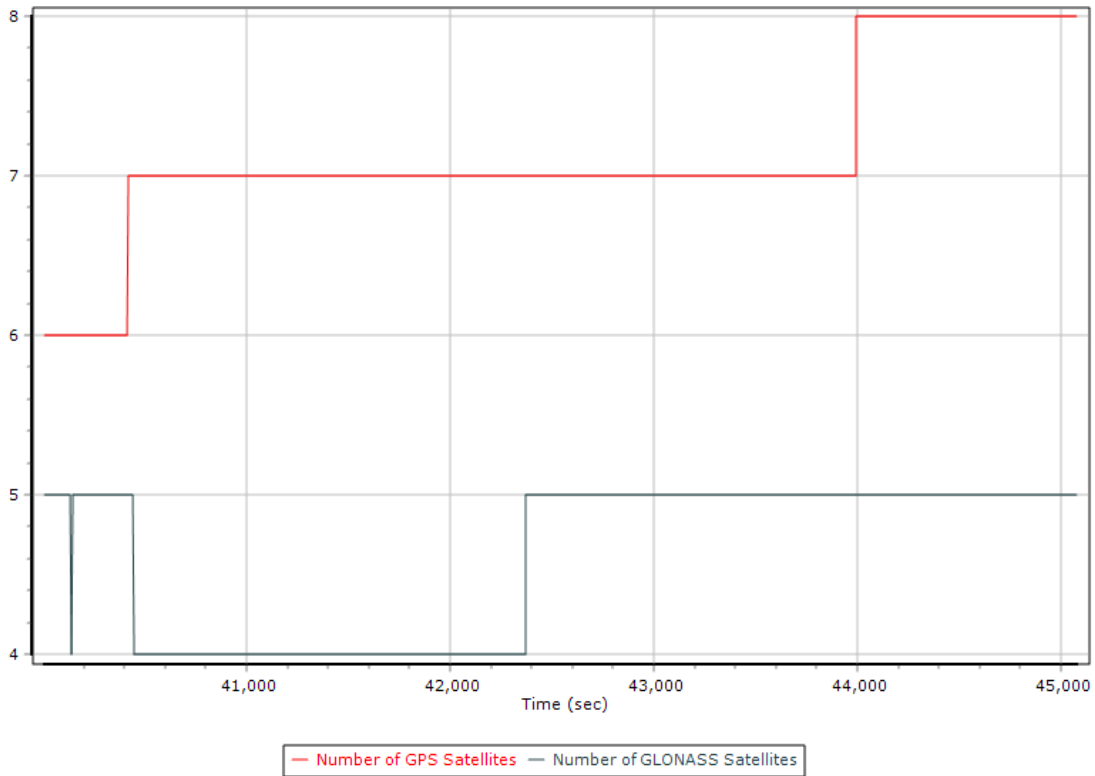


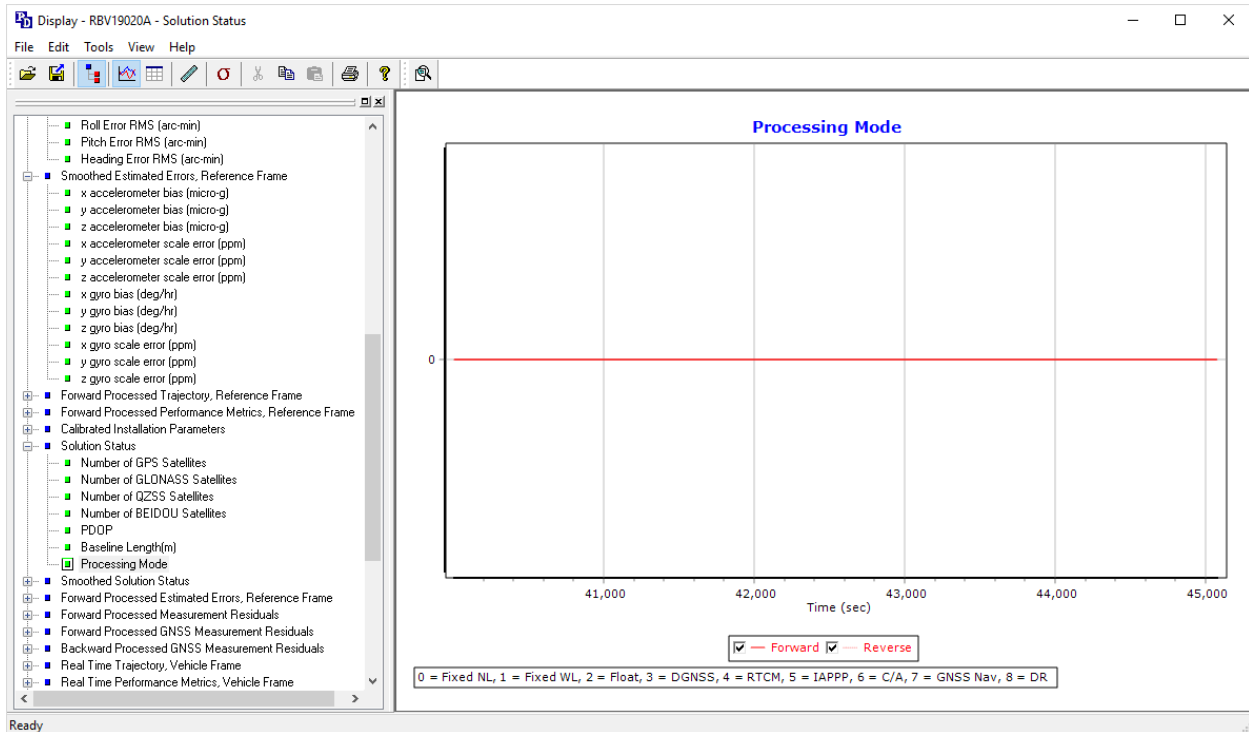
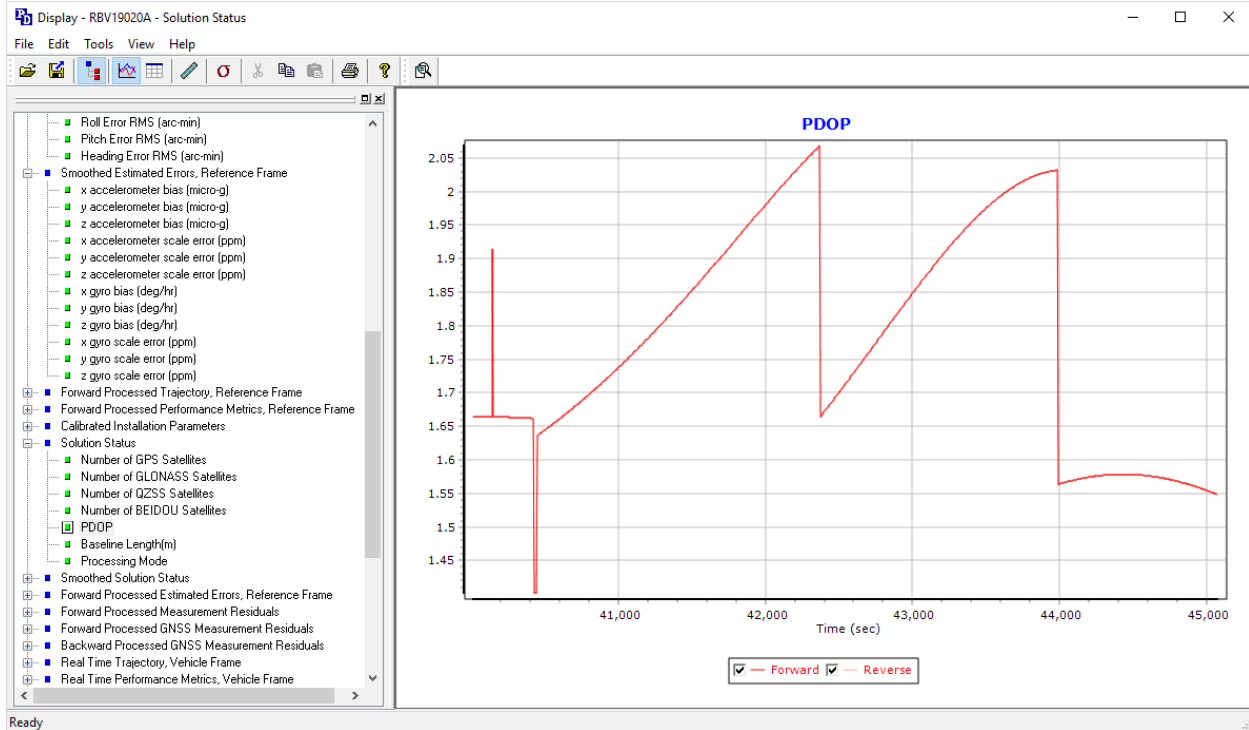
RBV19020A



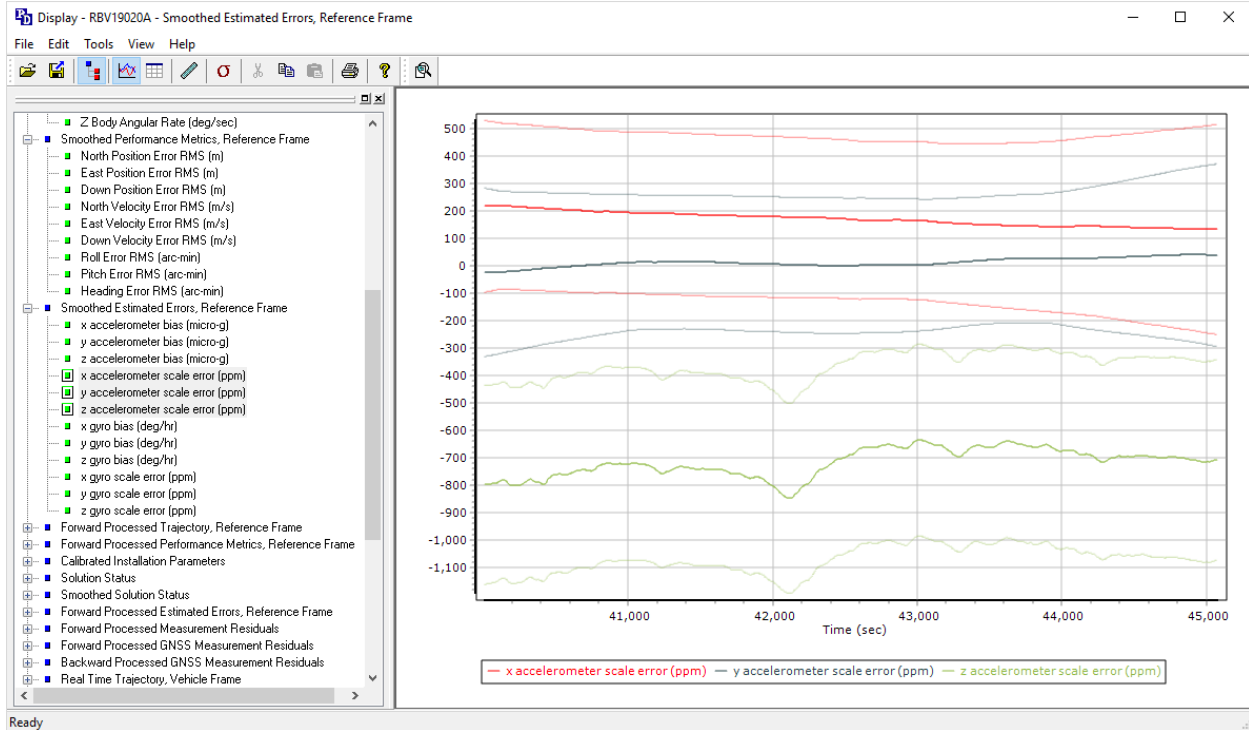
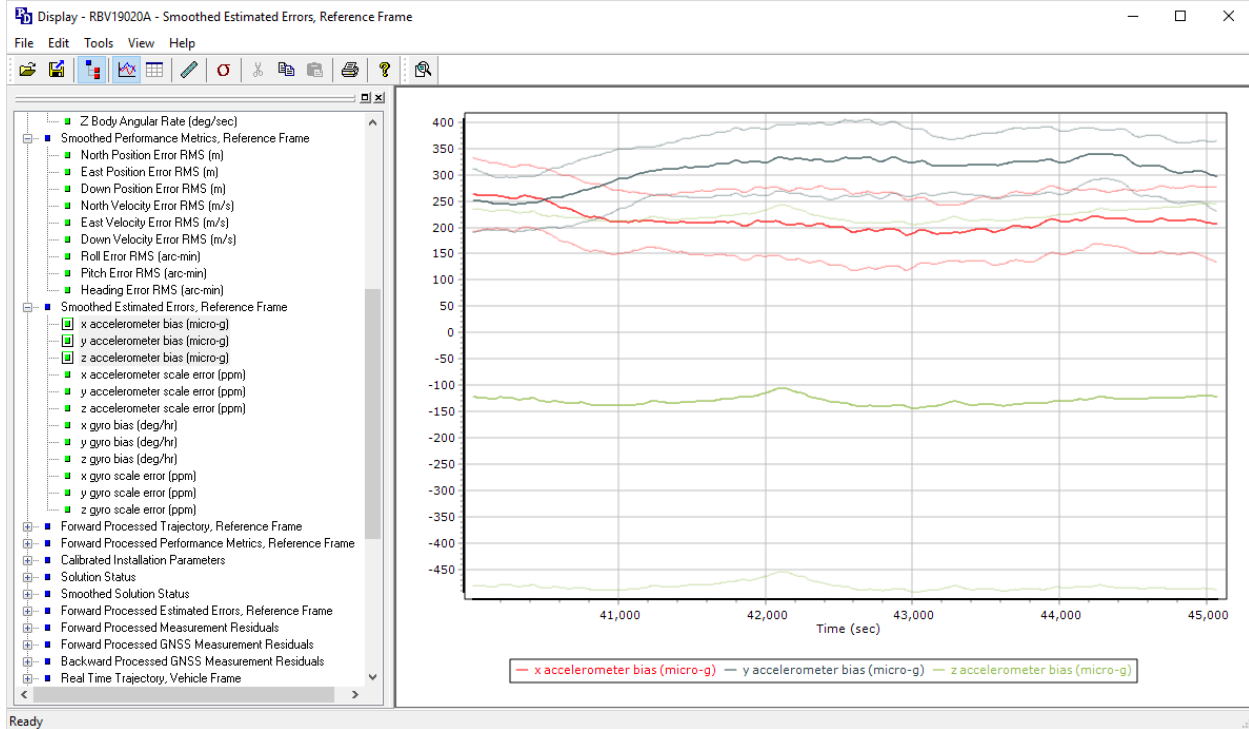


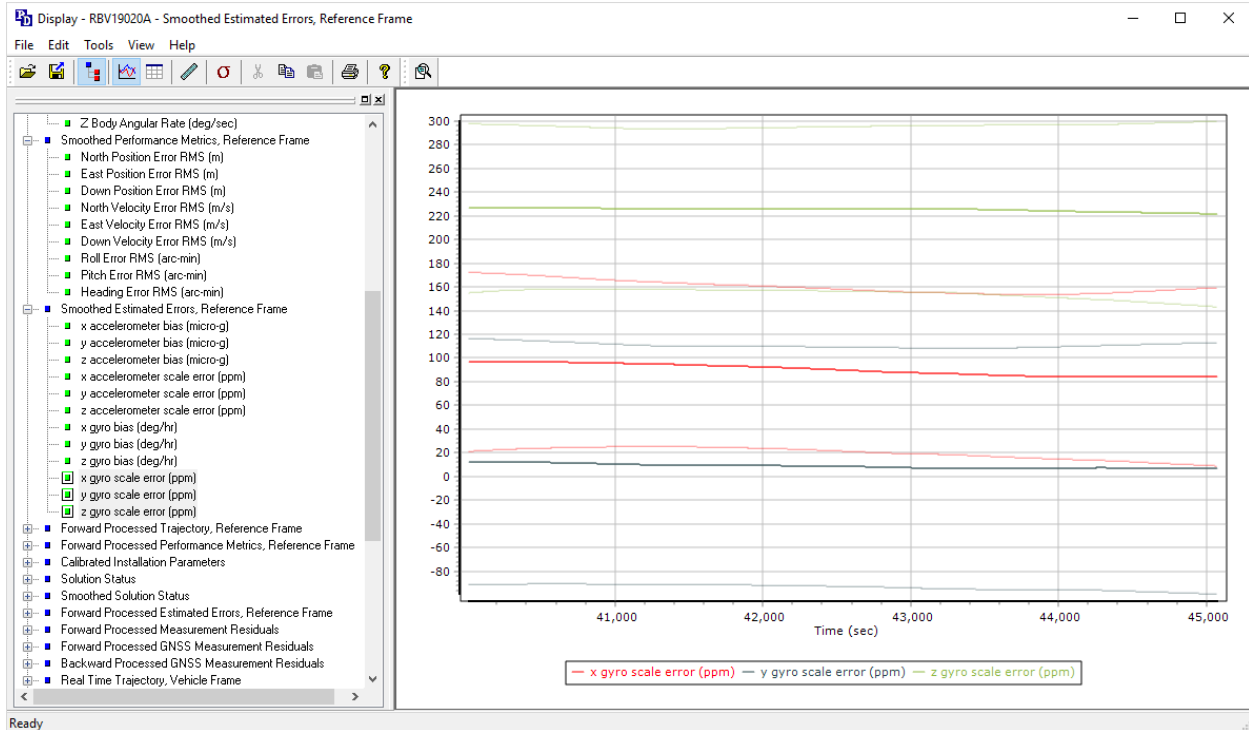
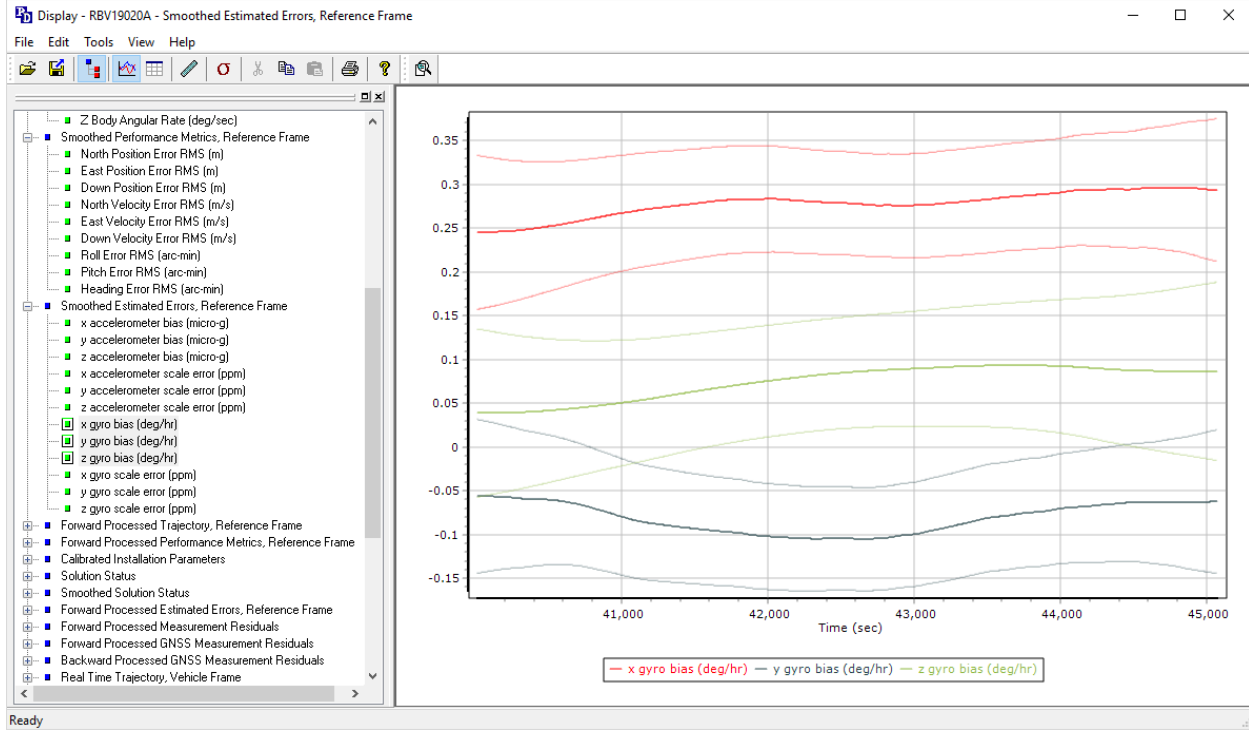




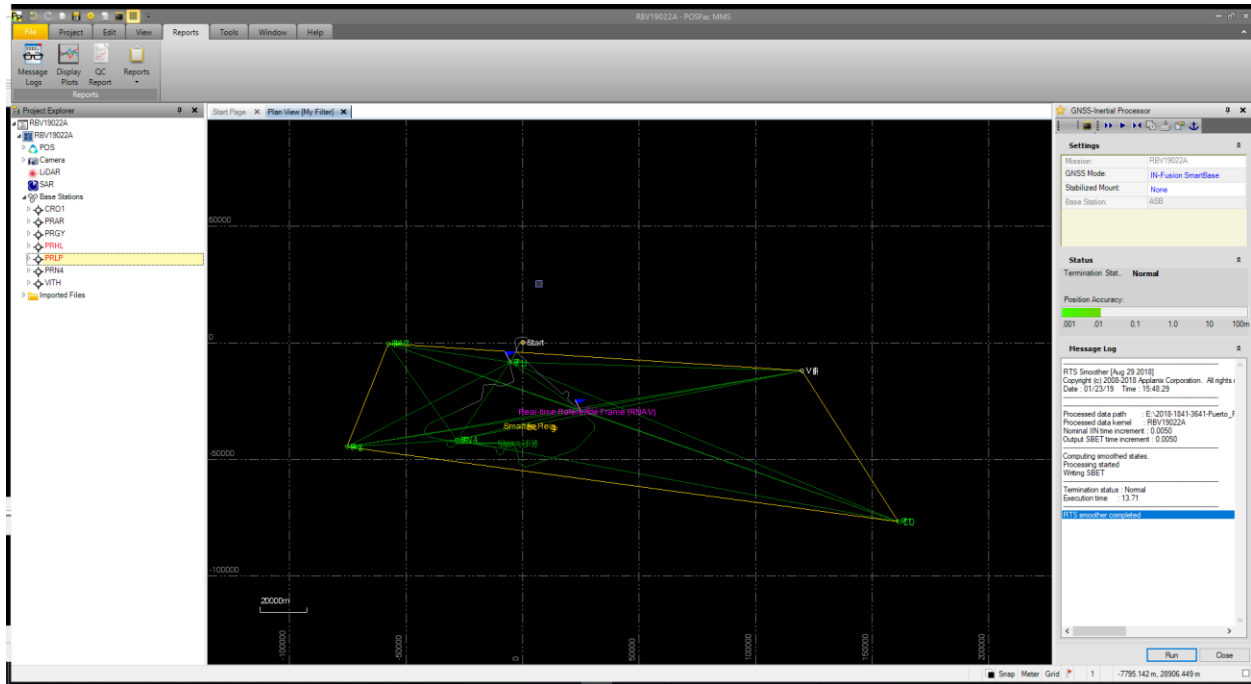


Sensor Errors





RBV19022A



Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNS3-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: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 m	Z: 0.000 deg

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

OK Cancel

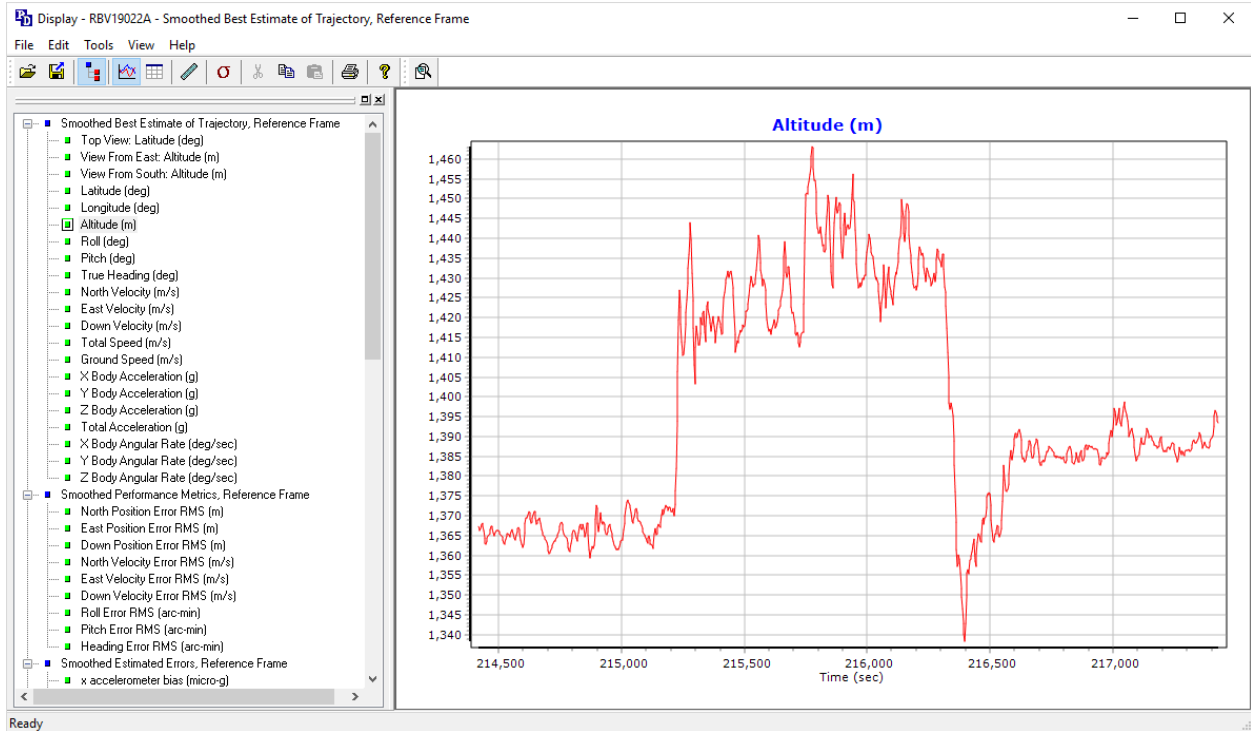
Project Settings

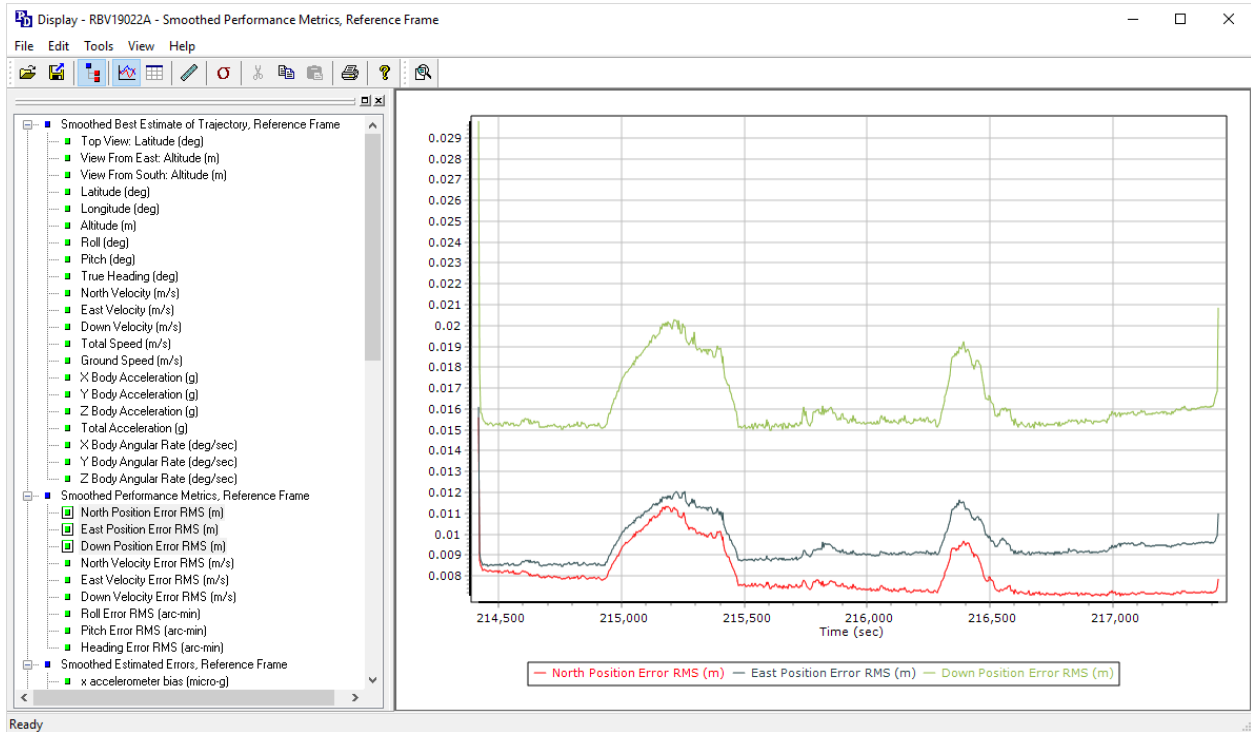
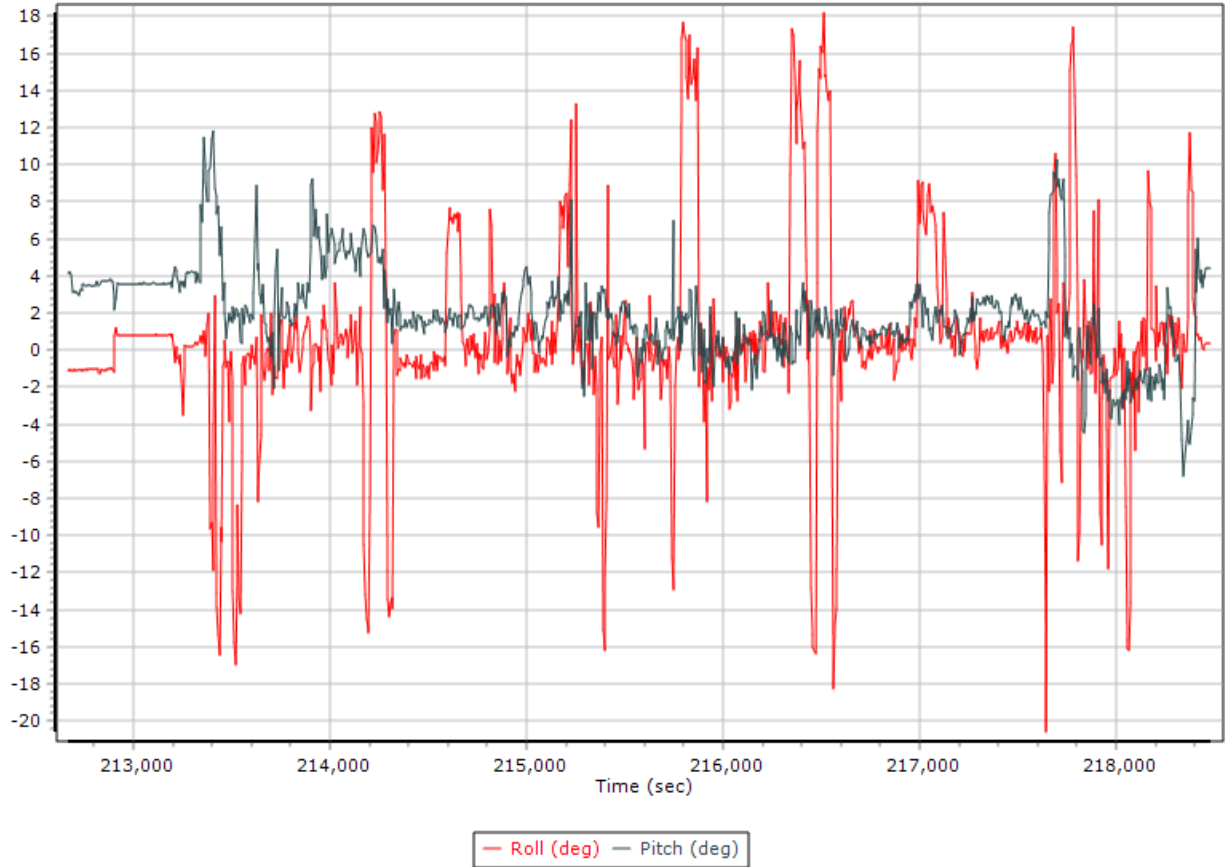
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
 Timing
 Algorithms
 Initialization
 Lever Arms and Mounting Angles
Export
Camera
LiDAR
SAR

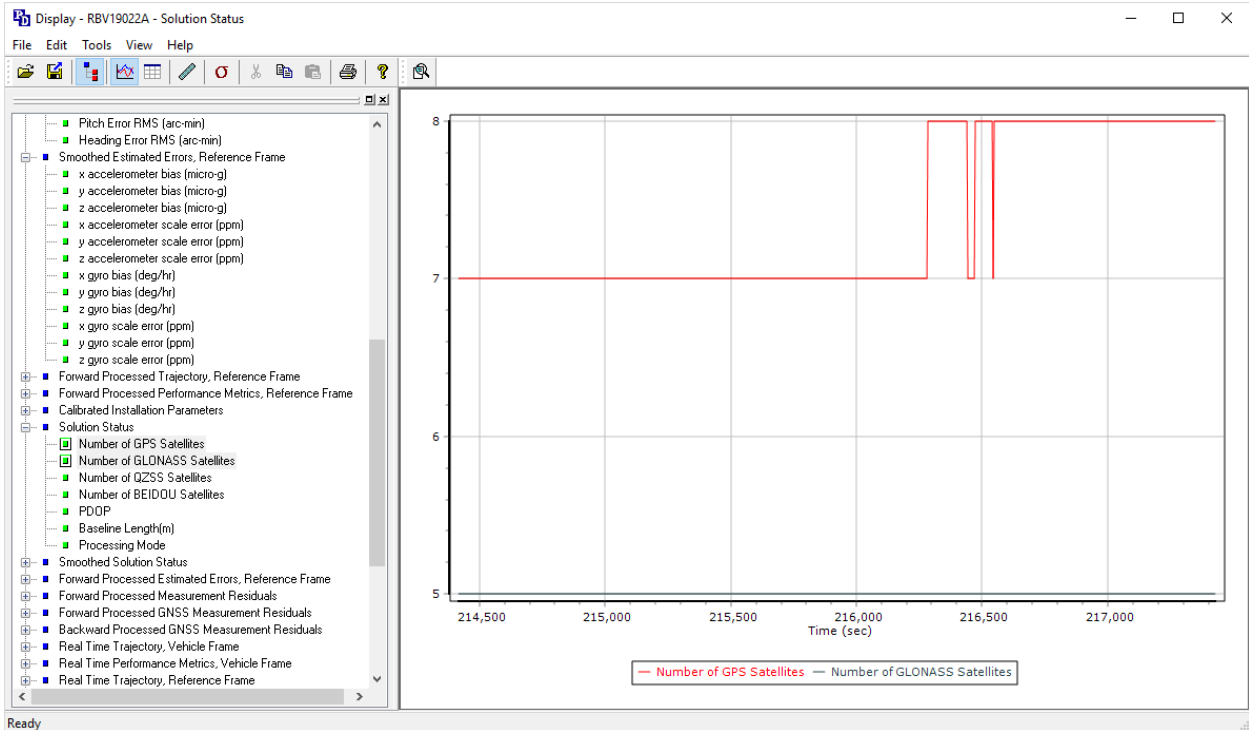
Timing
Start: 214414.237
End: 217432.909
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

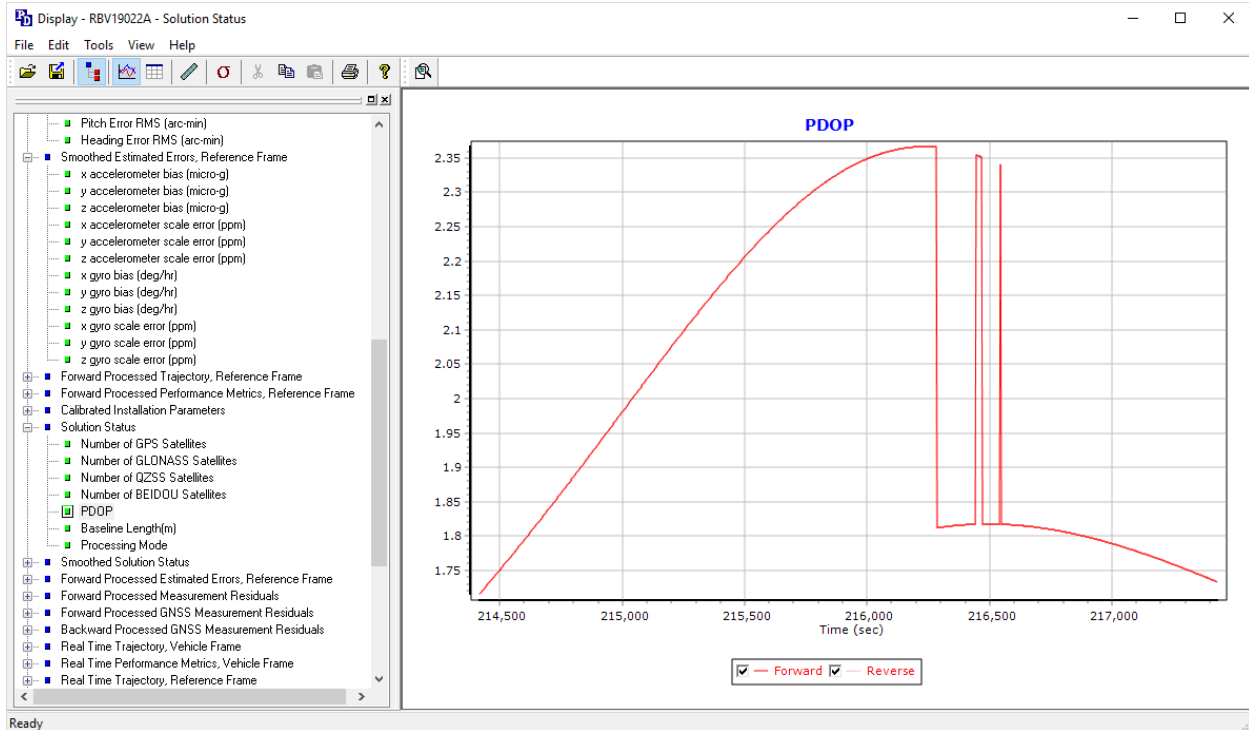
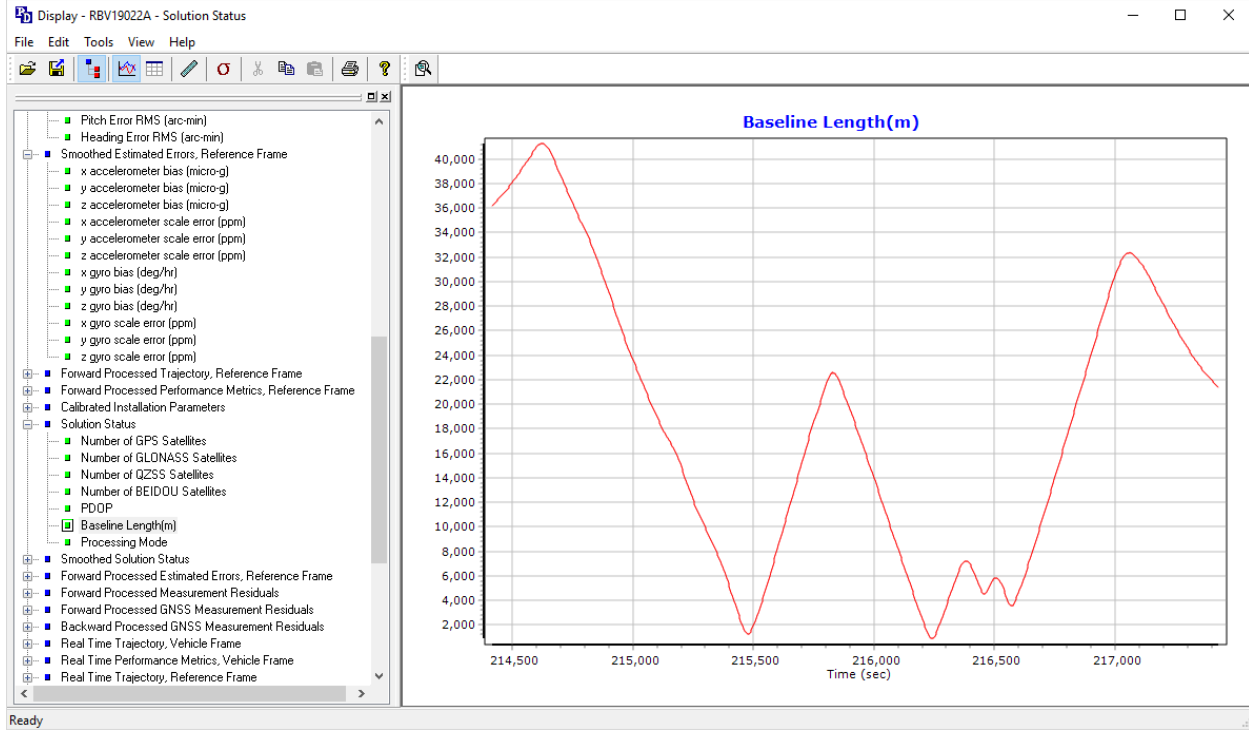
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

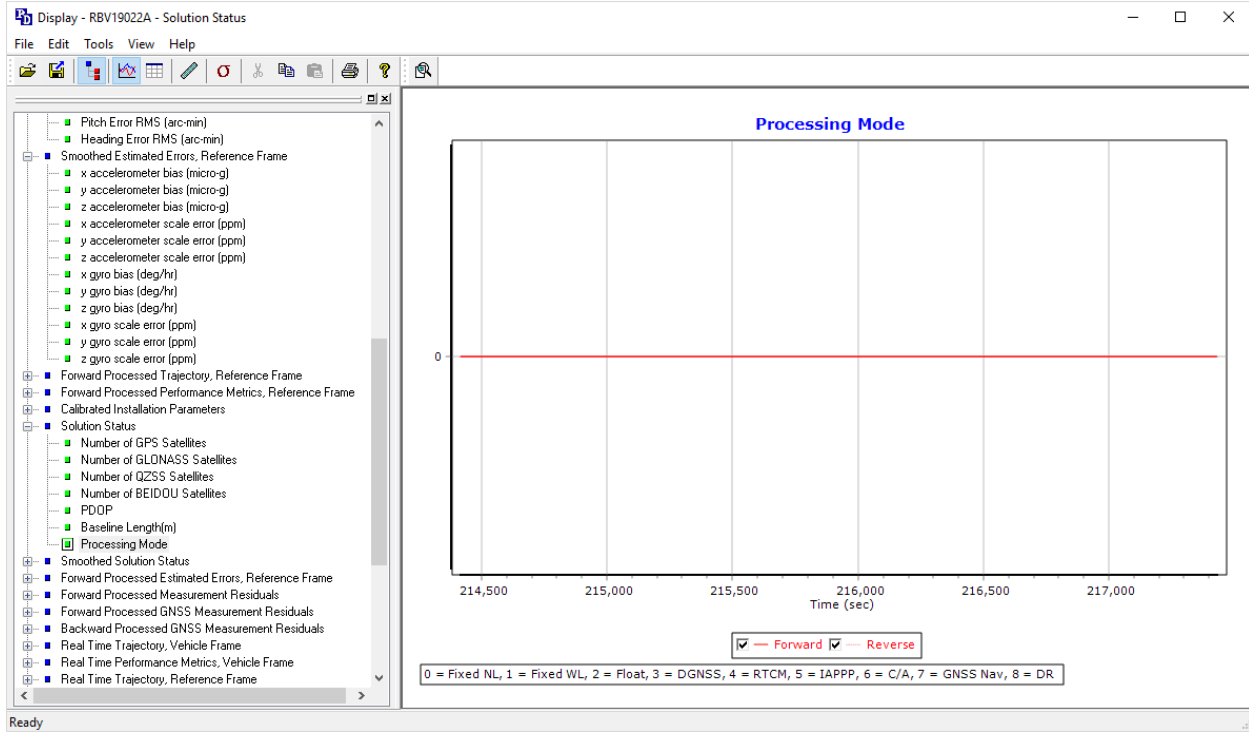
OK Cancel



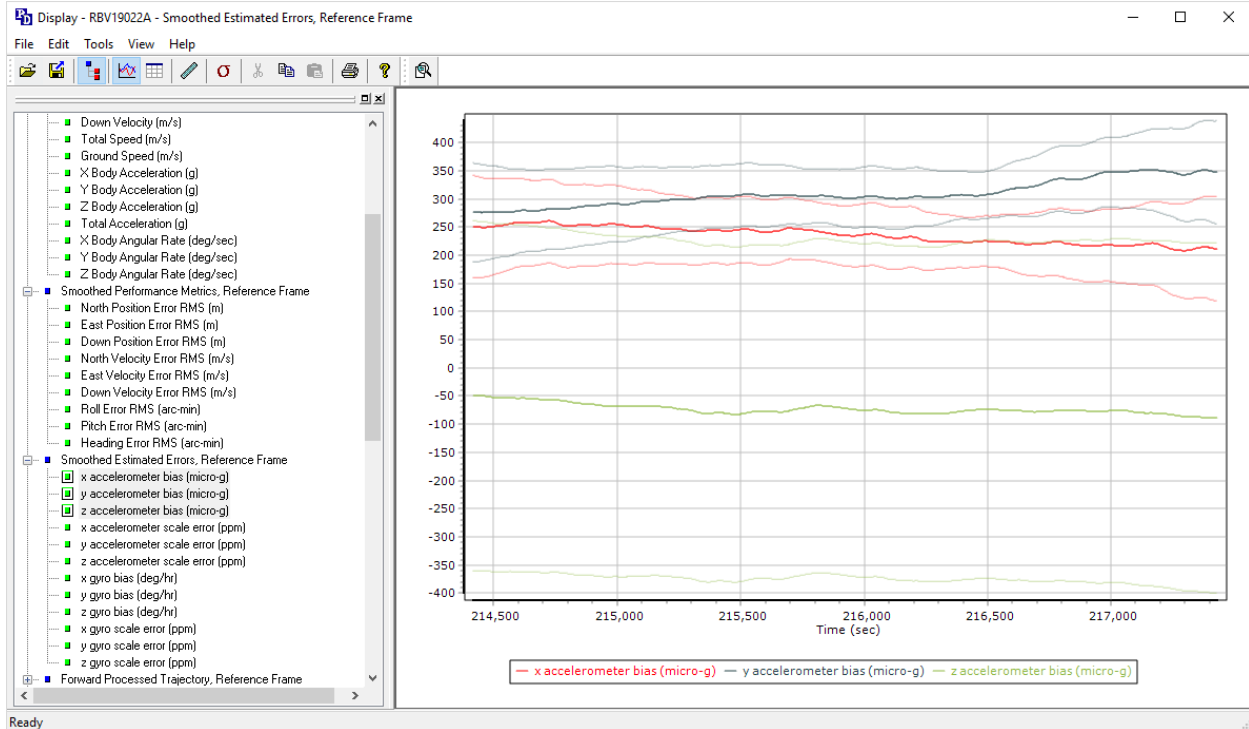


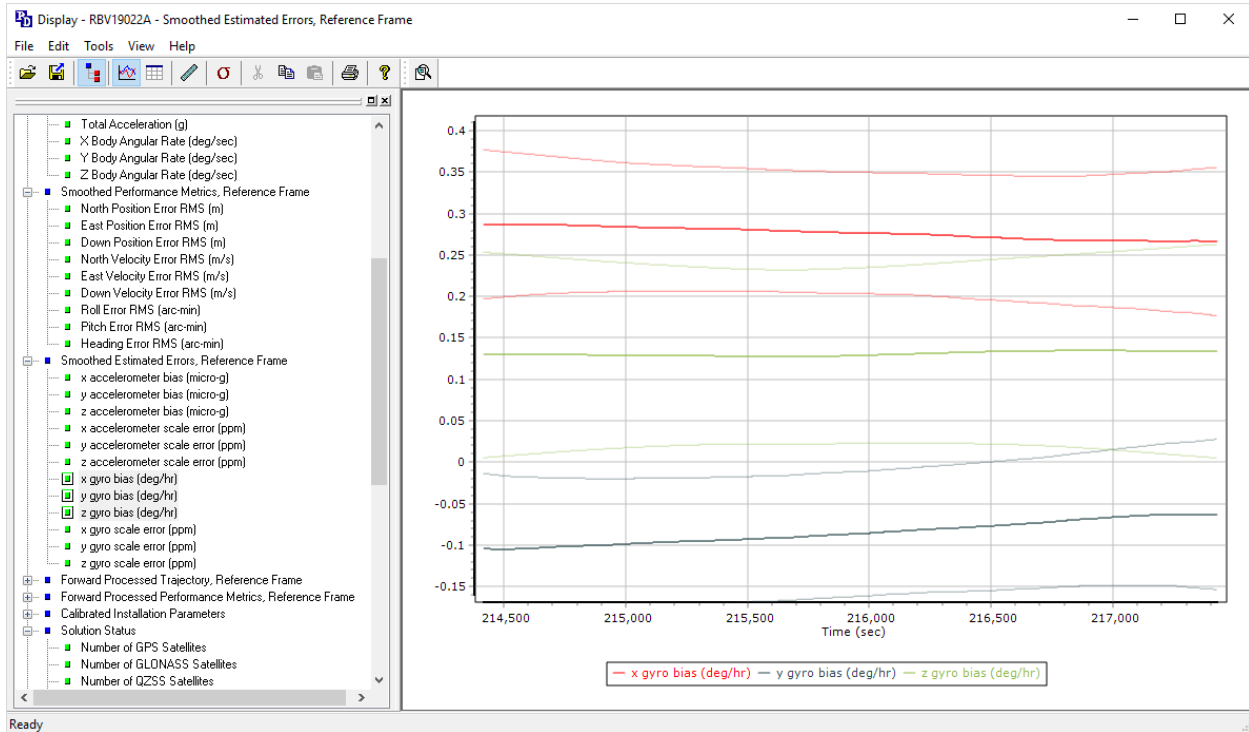
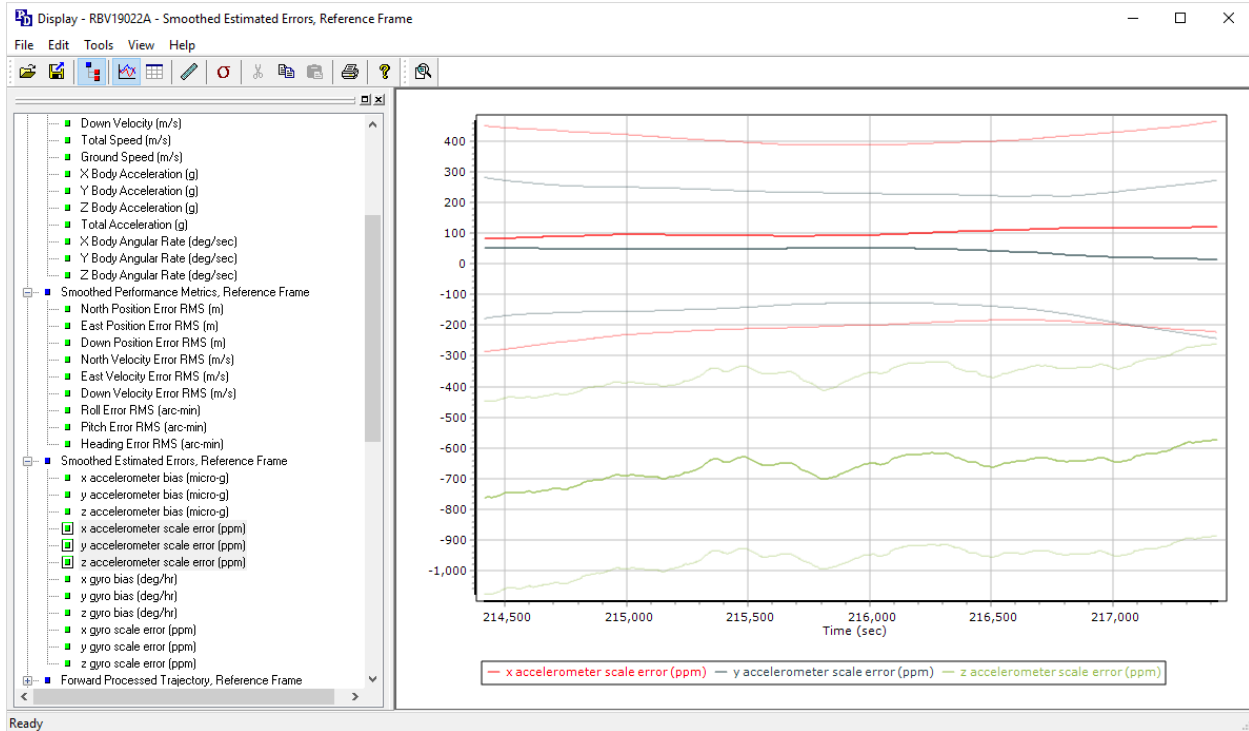


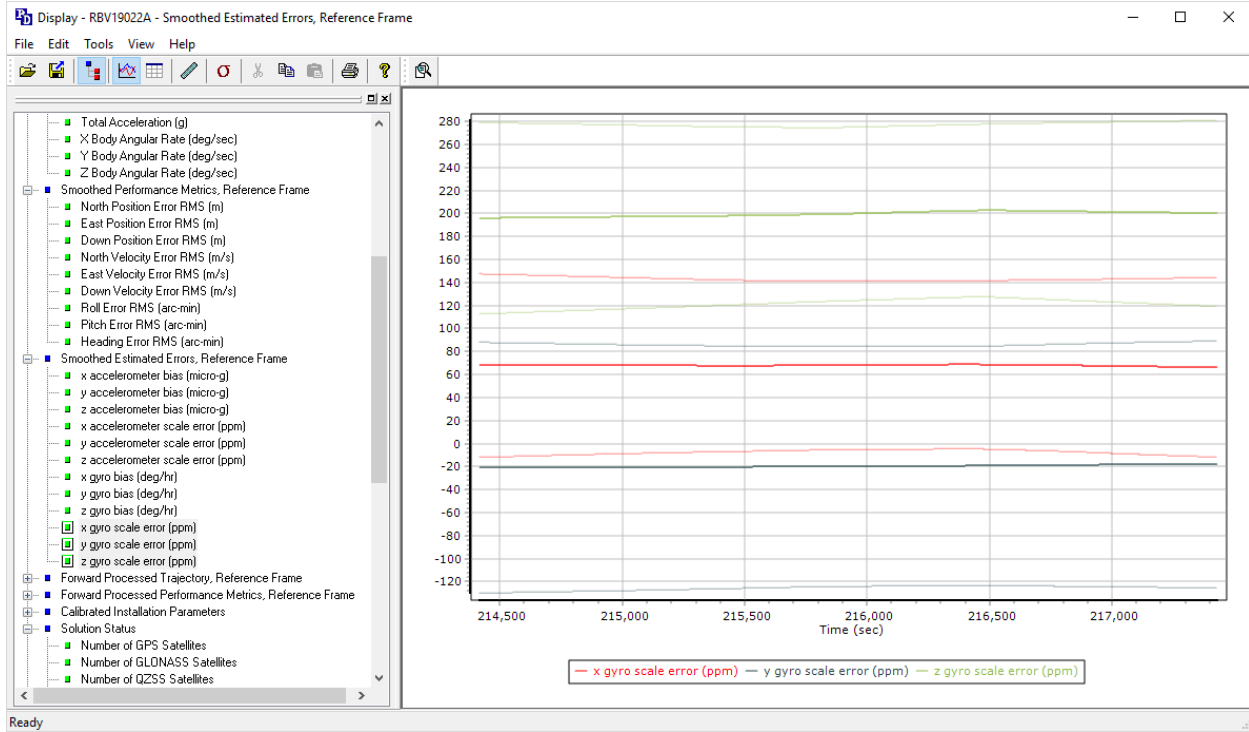




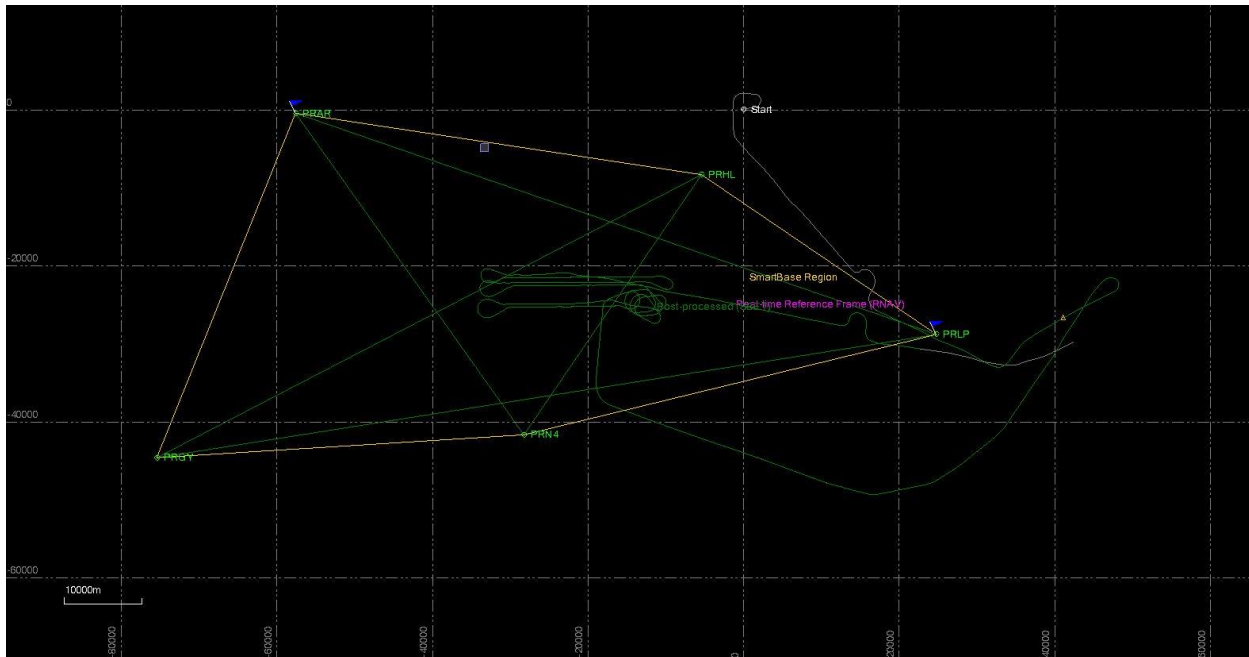
Sensor Errors







RBV19029A



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
X: 0.000 m
Y: 0.000 m
Z: 0.000 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: -0.024 m
Y: -0.001 m
Z: -0.742 m

Aircraft to Reference Mounting Angles
X: 0.000 deg
Y: 0.000 deg
Z: 0.000 deg

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

OK Cancel

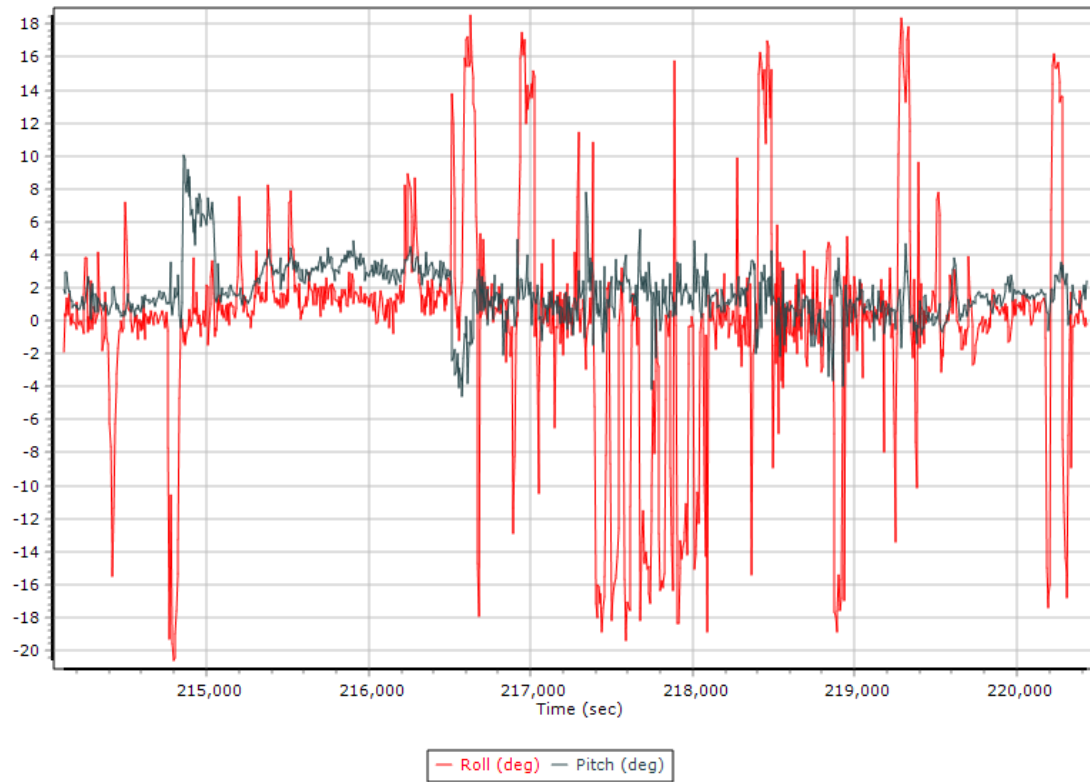
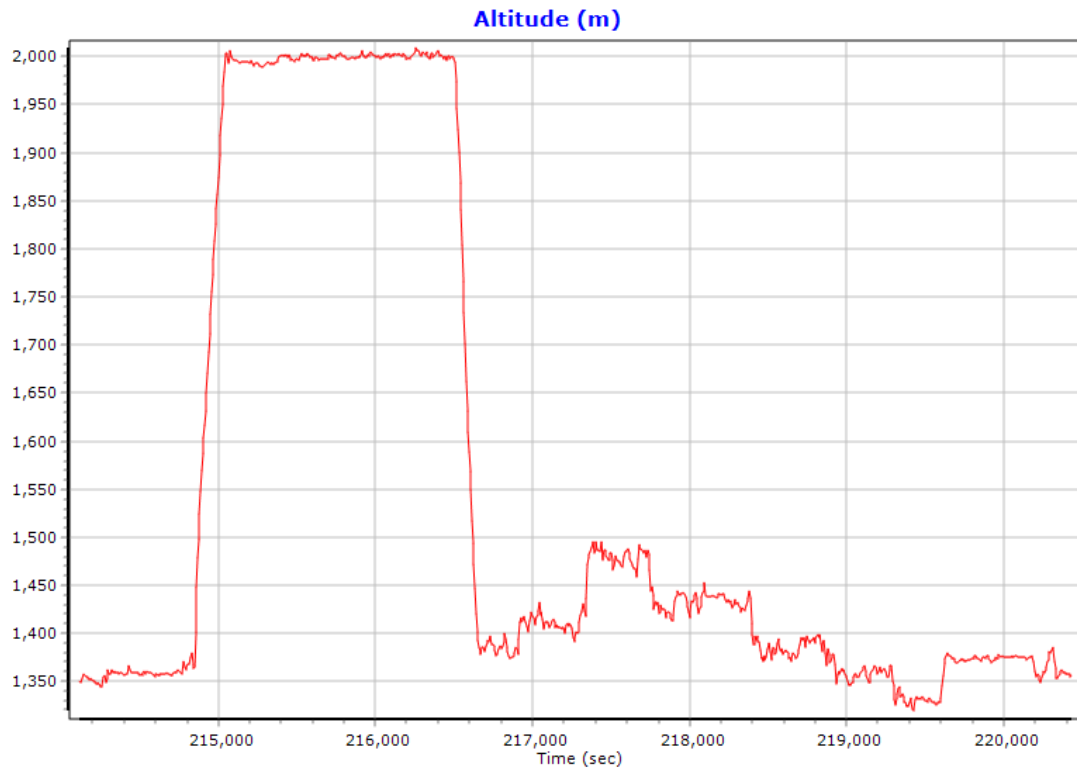
Project Settings

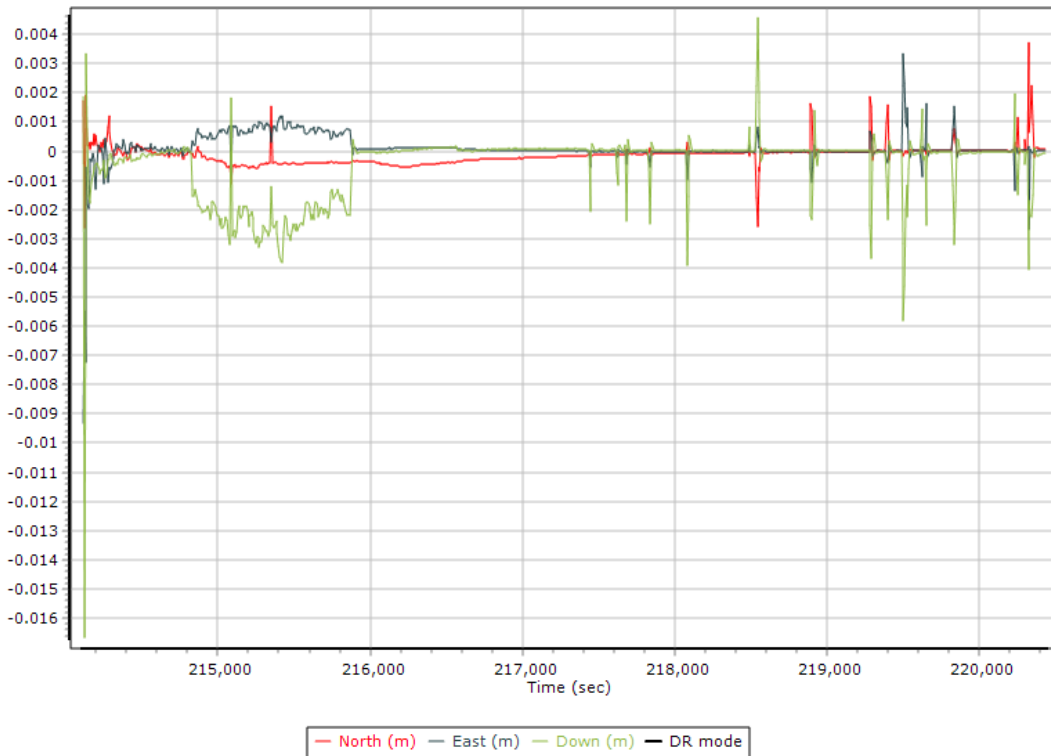
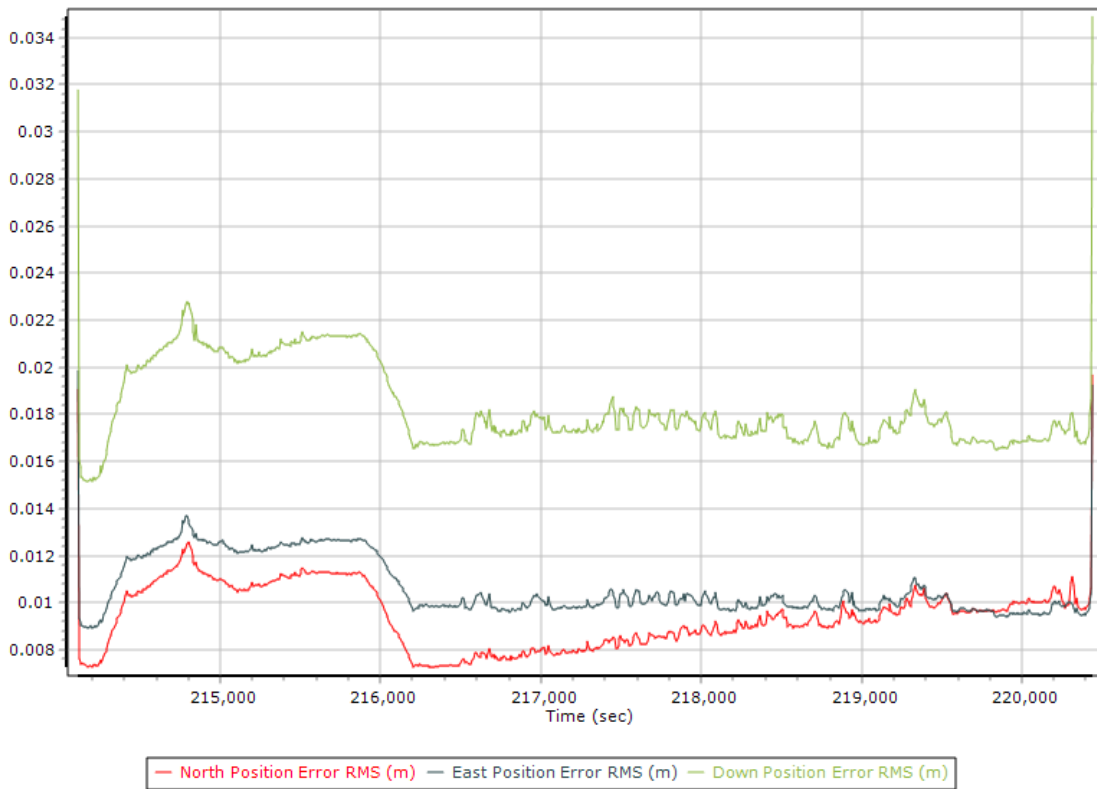
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
 Timing
 Algorithms
 Initialization
 Lever Arms and Mounting Angles
Export
Camera
LiDAR
SAR

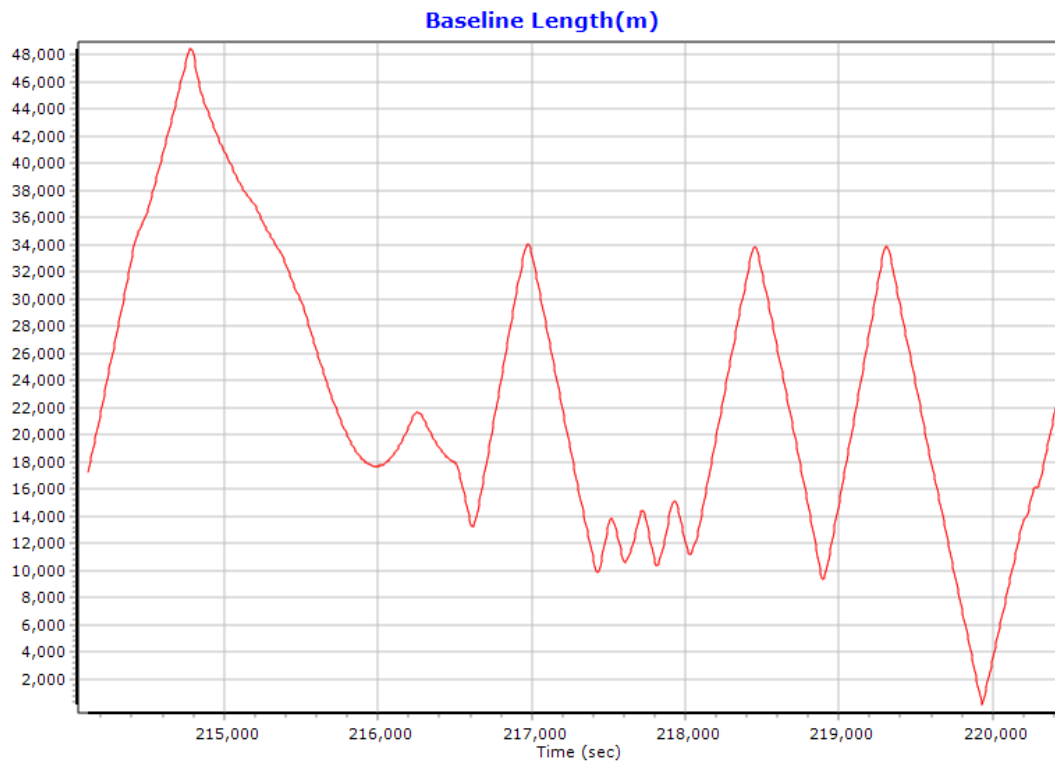
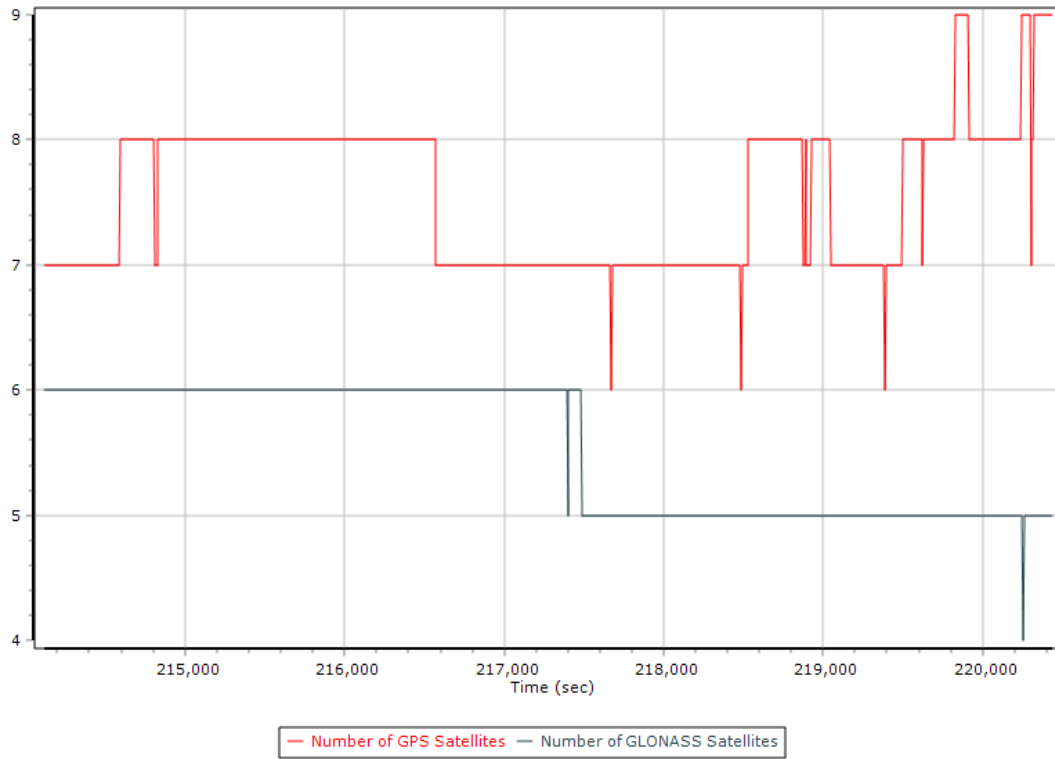
Timing
Start: 214113.682
End: 220435.999
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

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

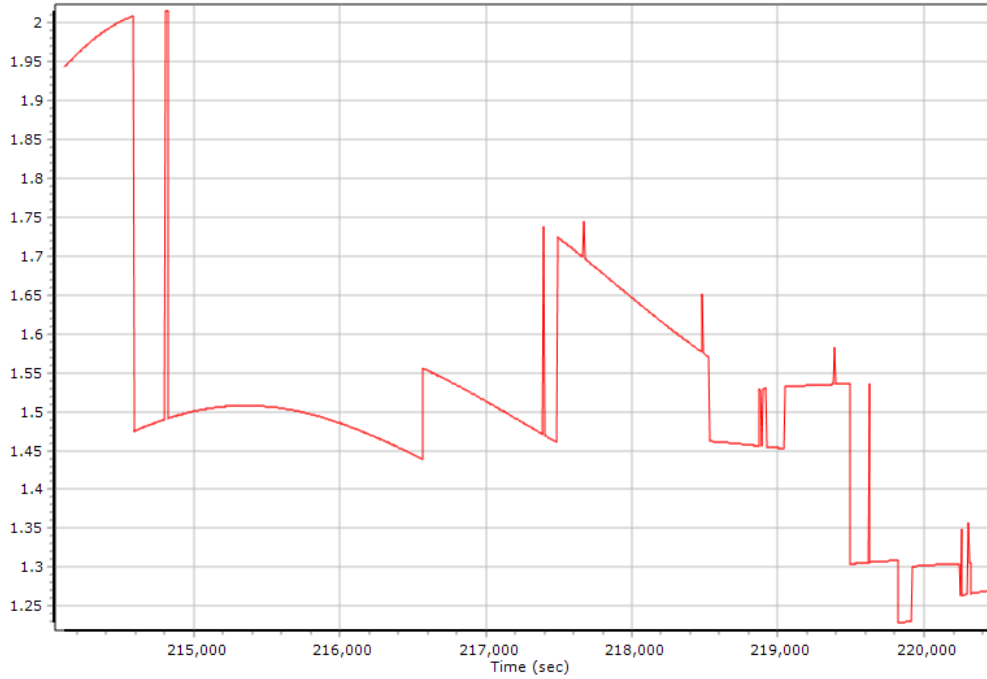
OK Cancel



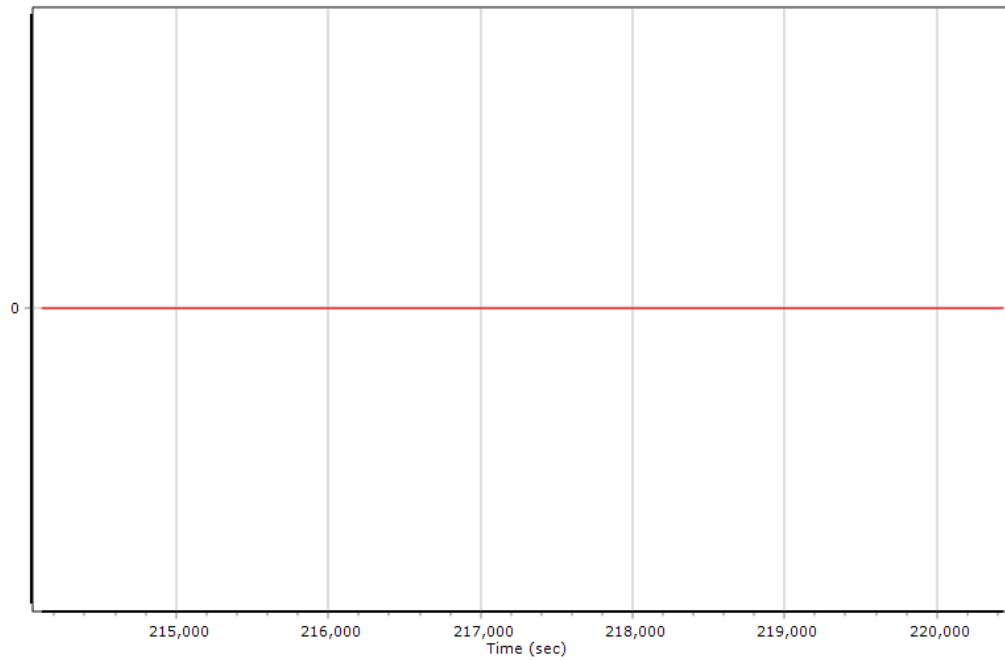




PDOP

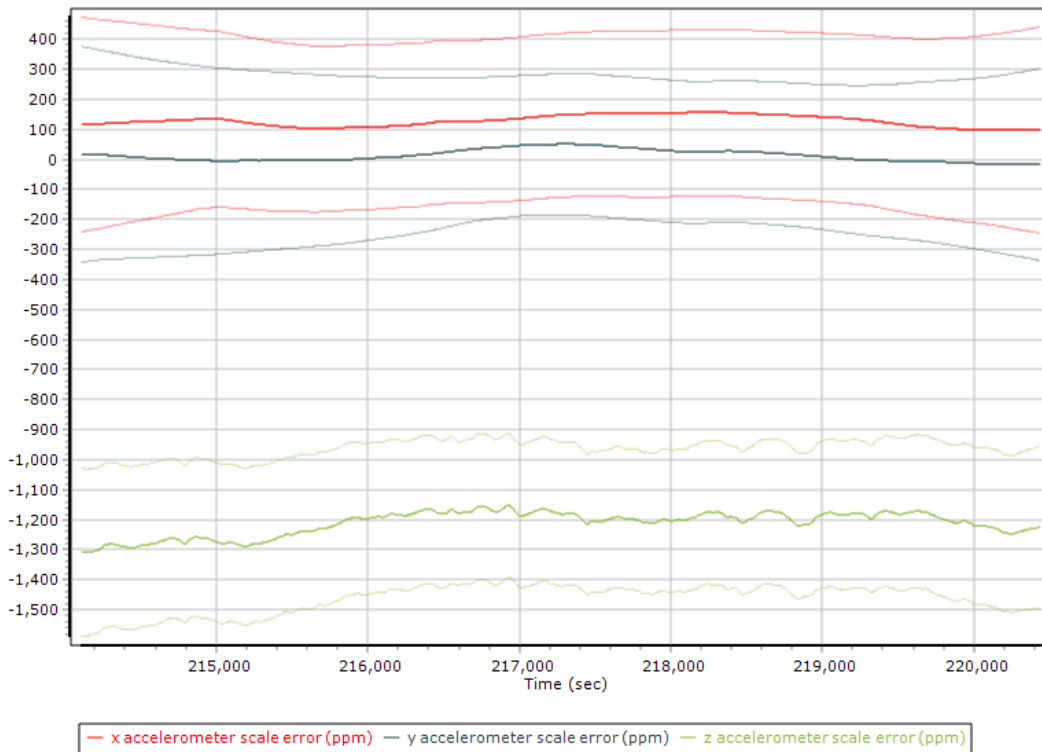
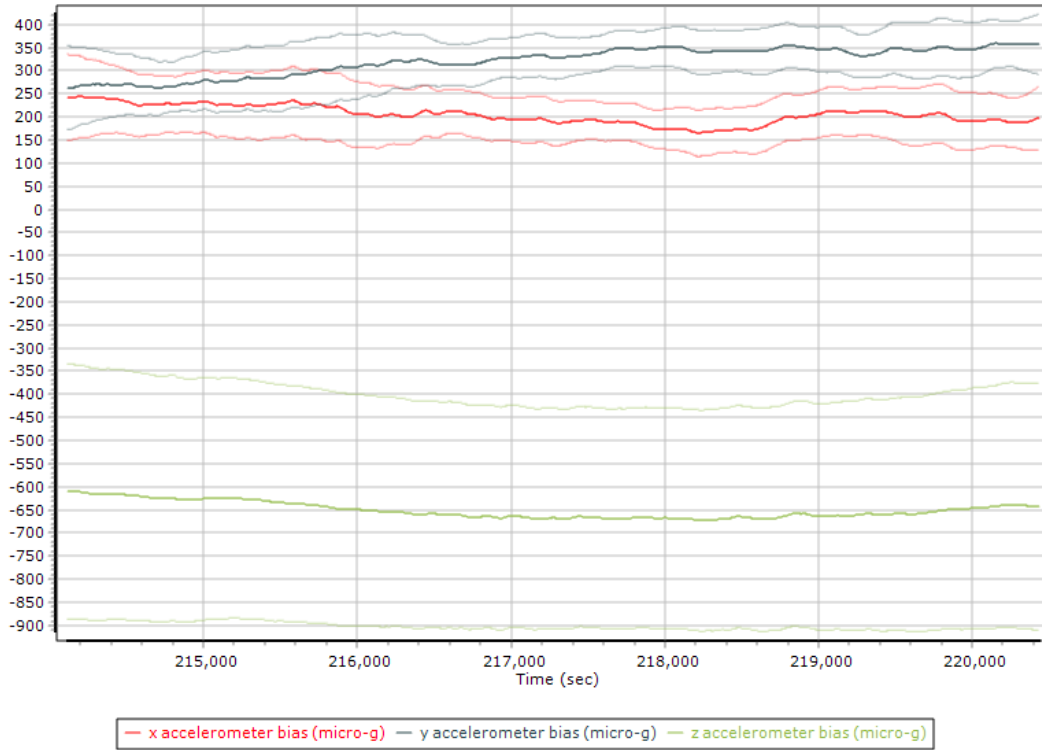


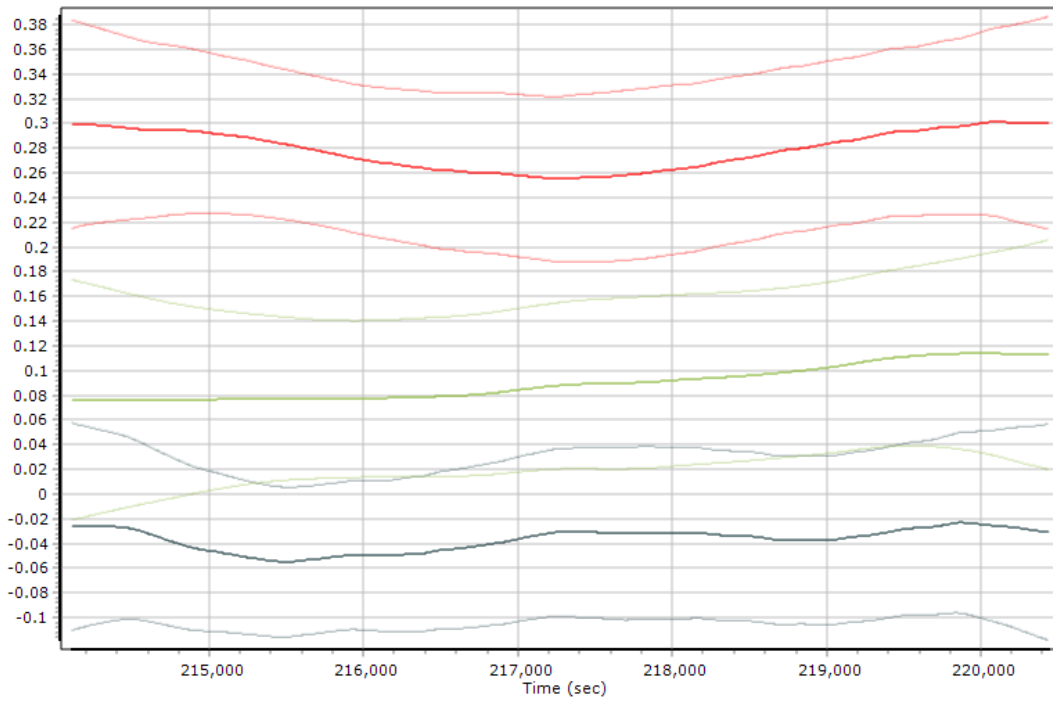
Processing Mode



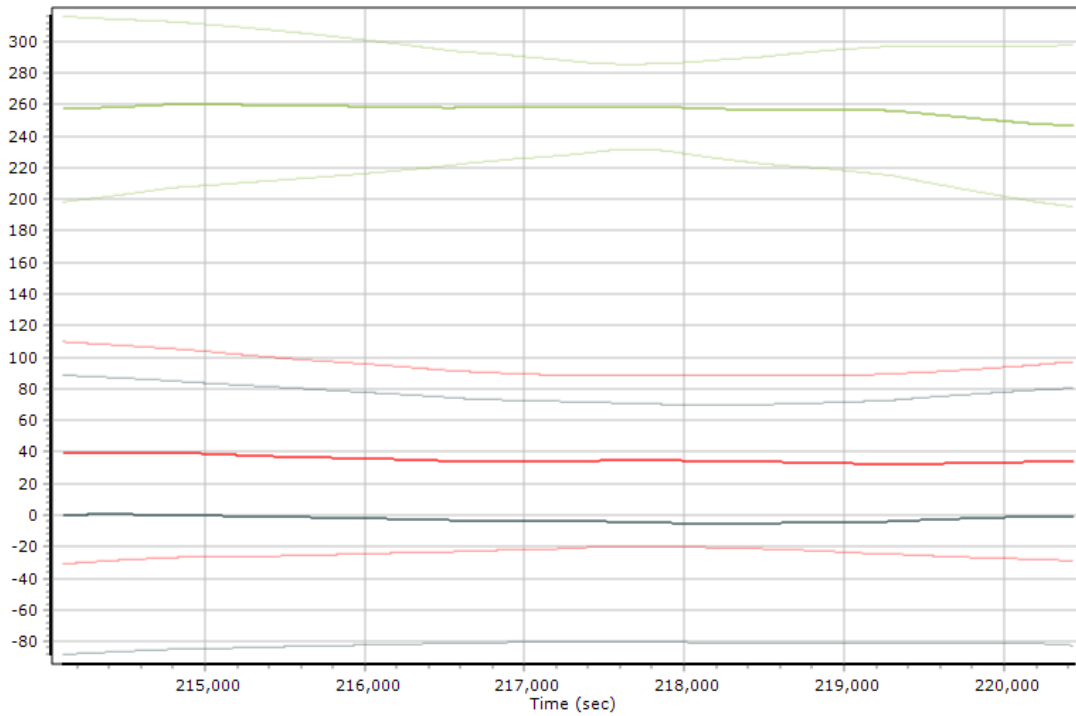
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors



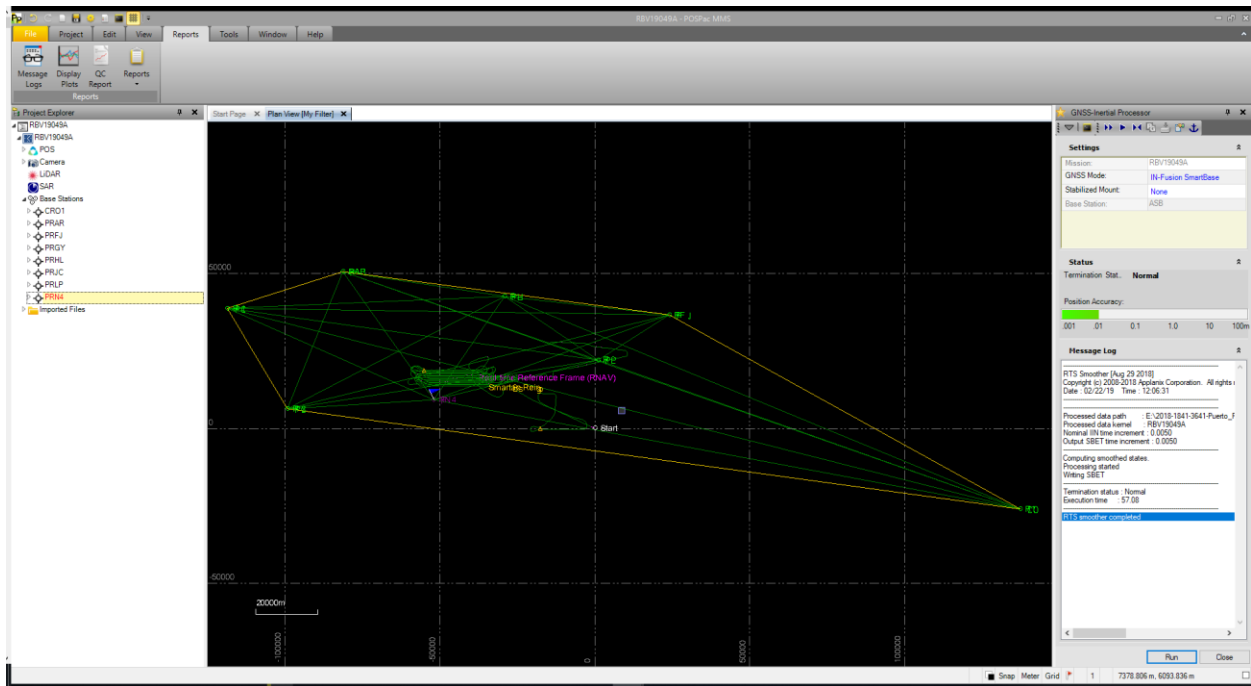


x gyro bias (deg/hr) y gyro bias (deg/hr) z gyro bias (deg/hr)



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

RBV19049A



Project Settings

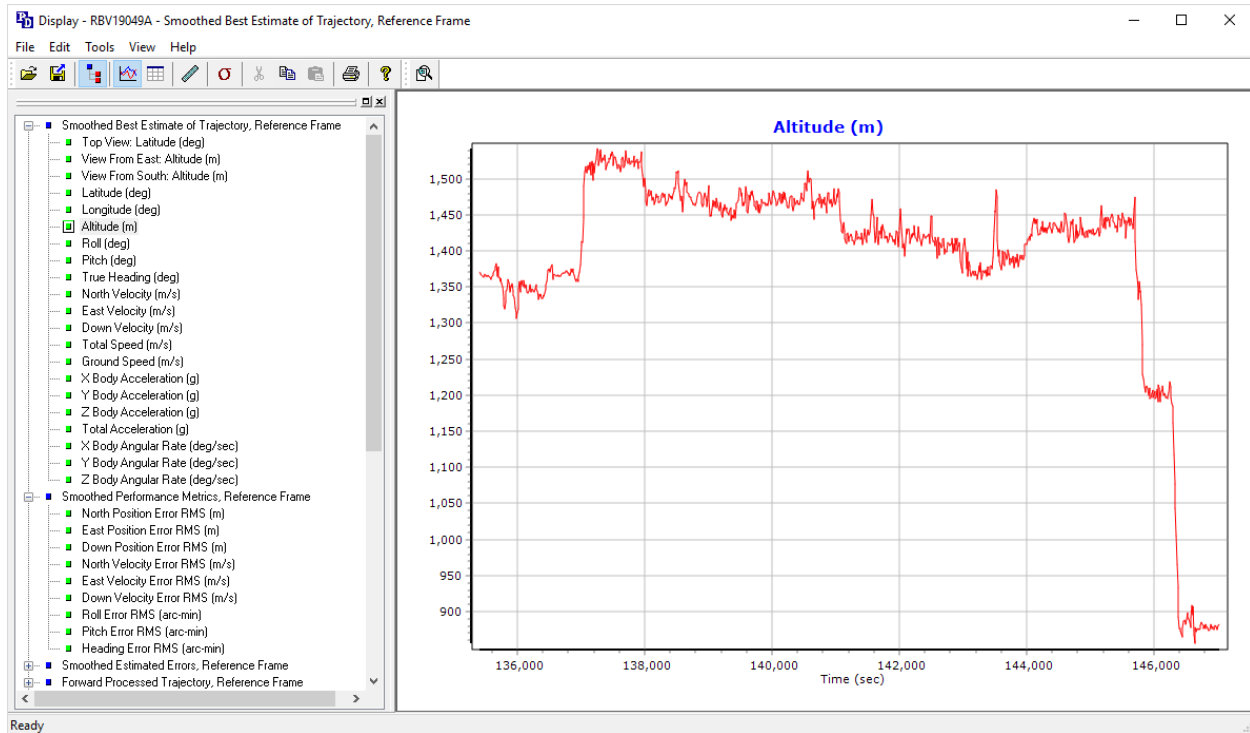
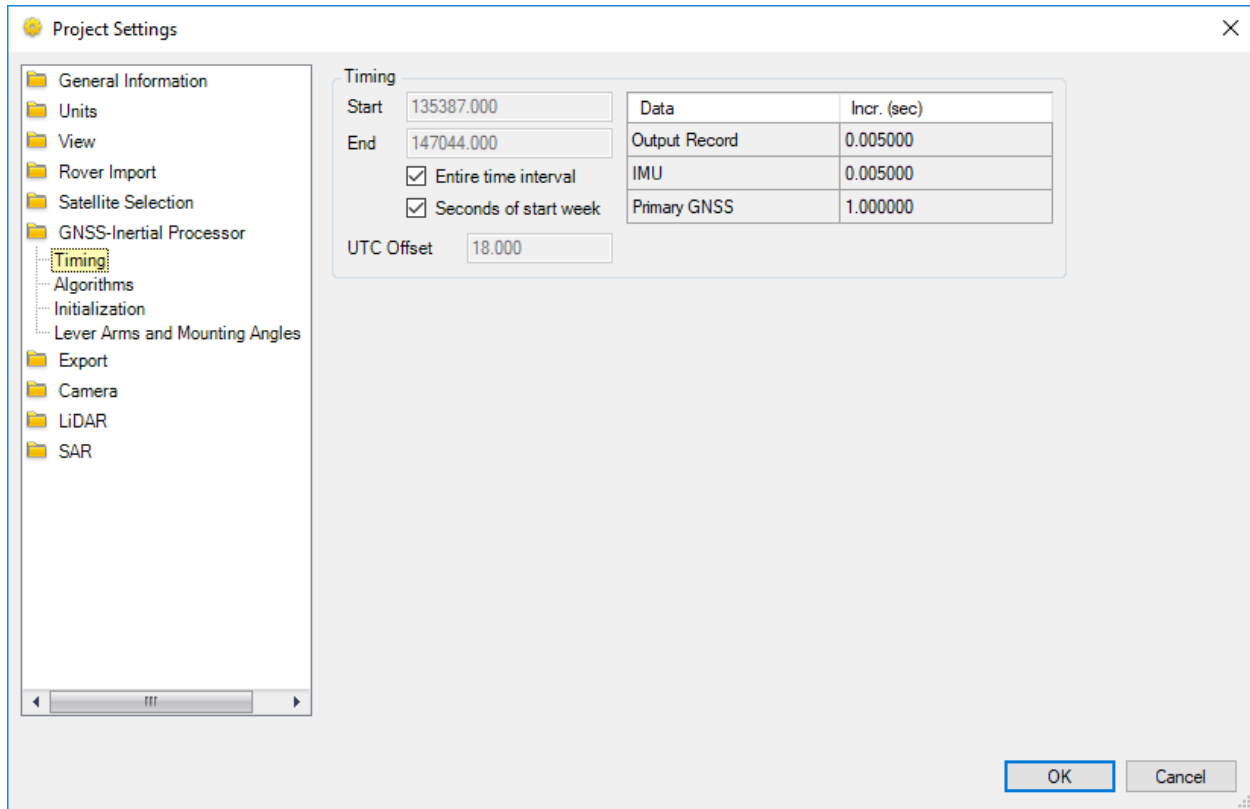
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LIDAR
- SAR

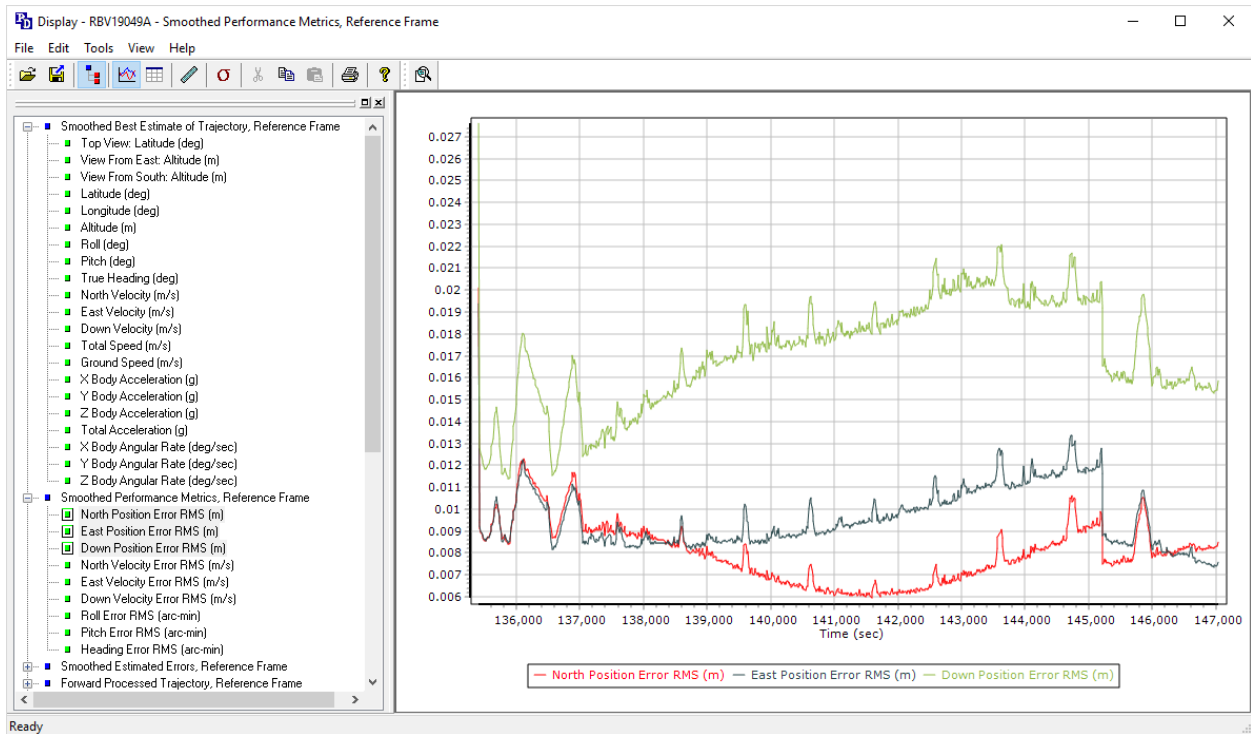
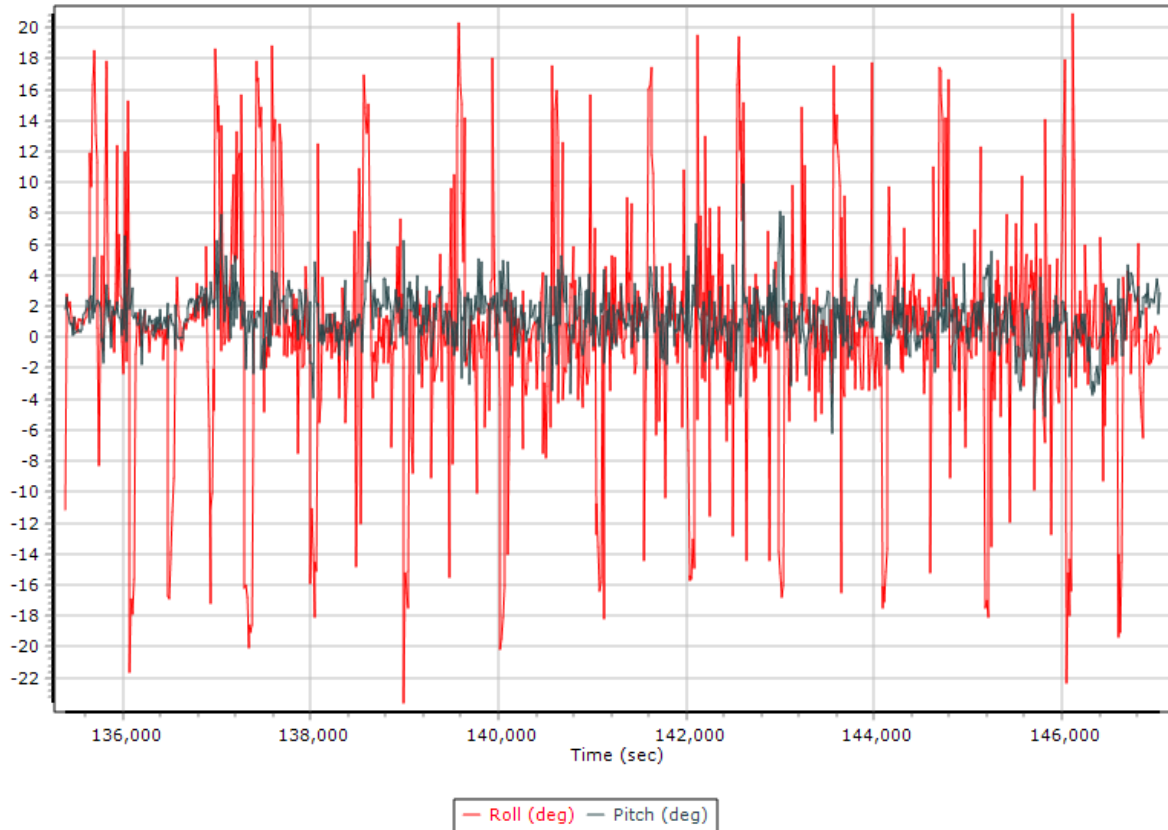
Reference to IMU Lever Arm	Reference to IMU Mounting Angles
X: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

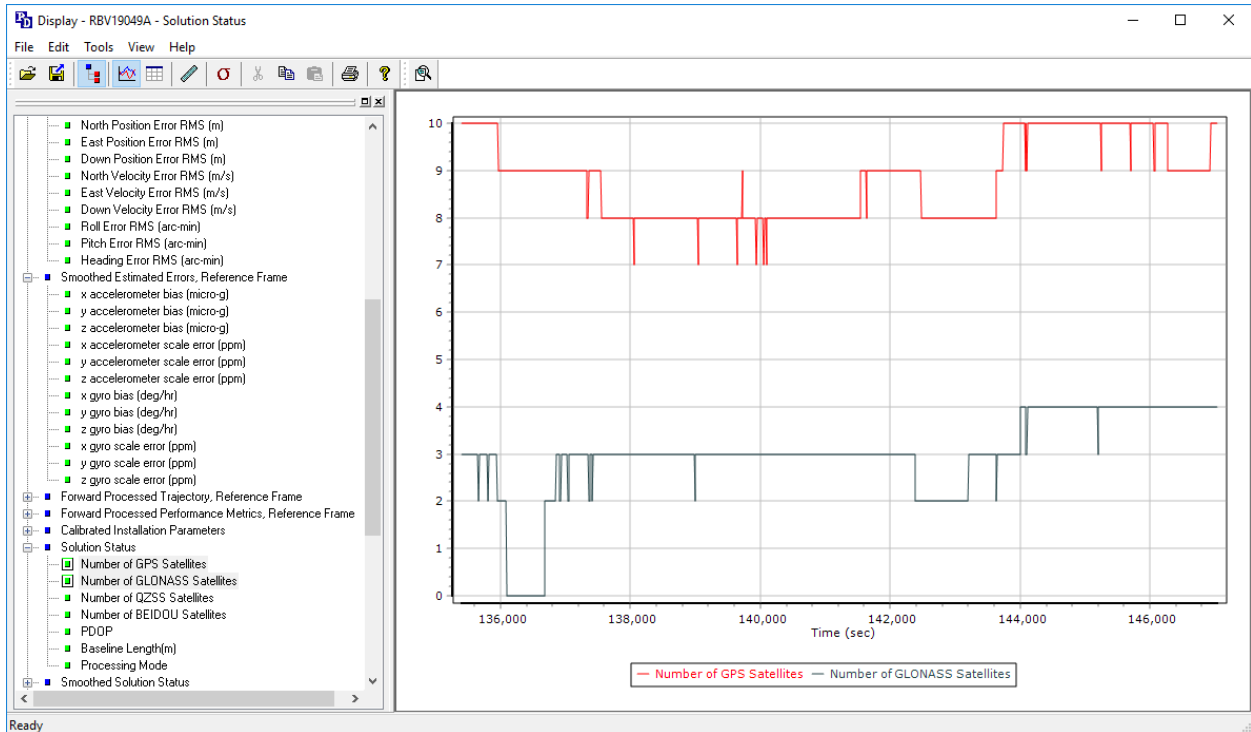
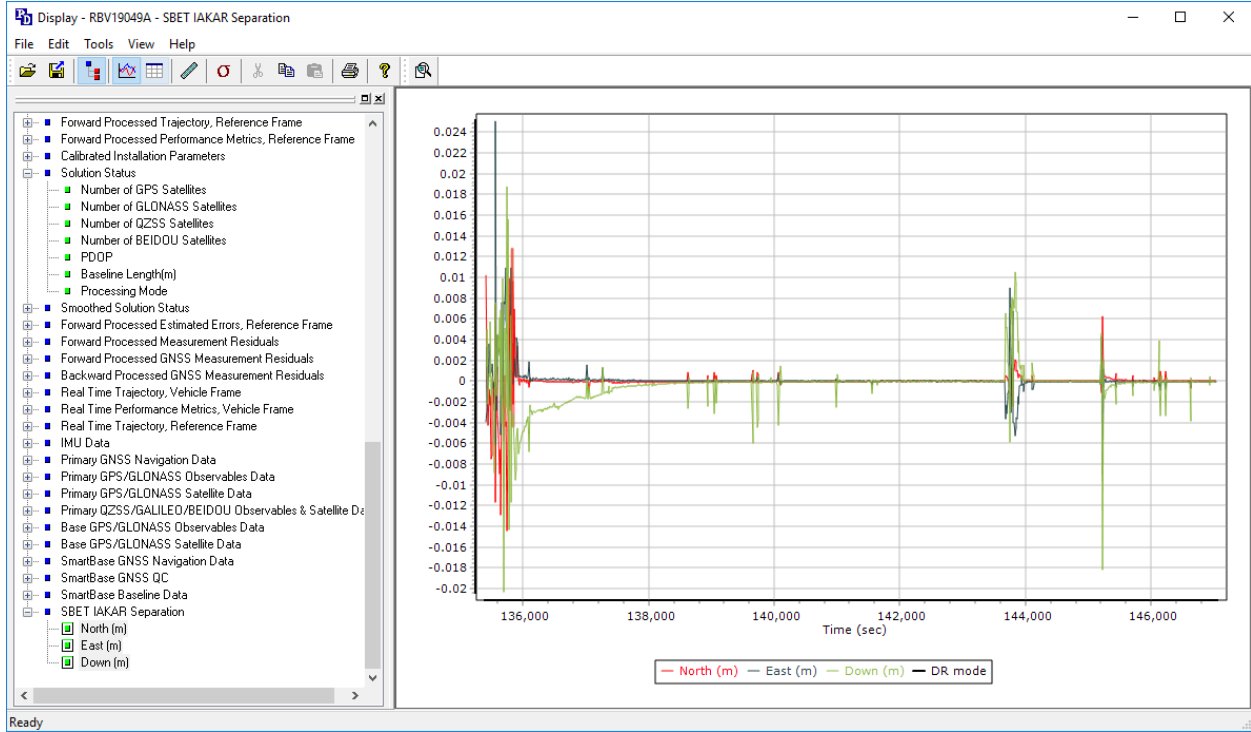
Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 m	Z: 0.000 deg

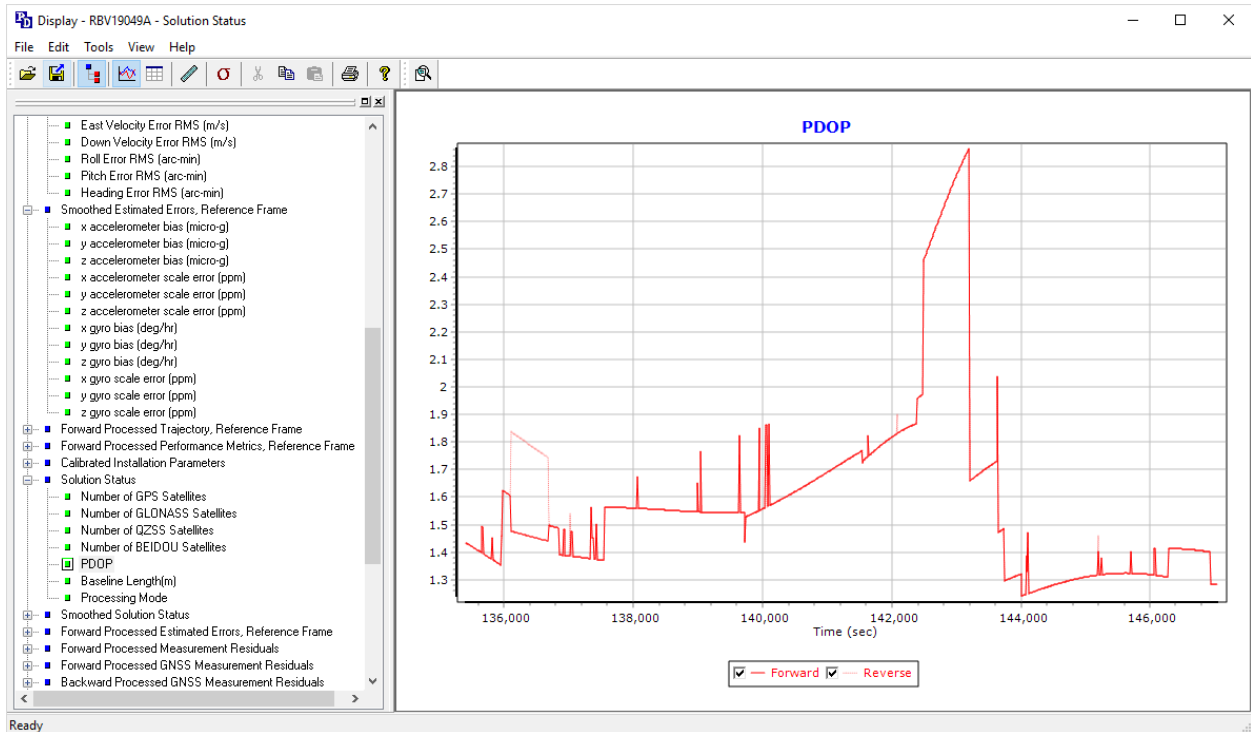
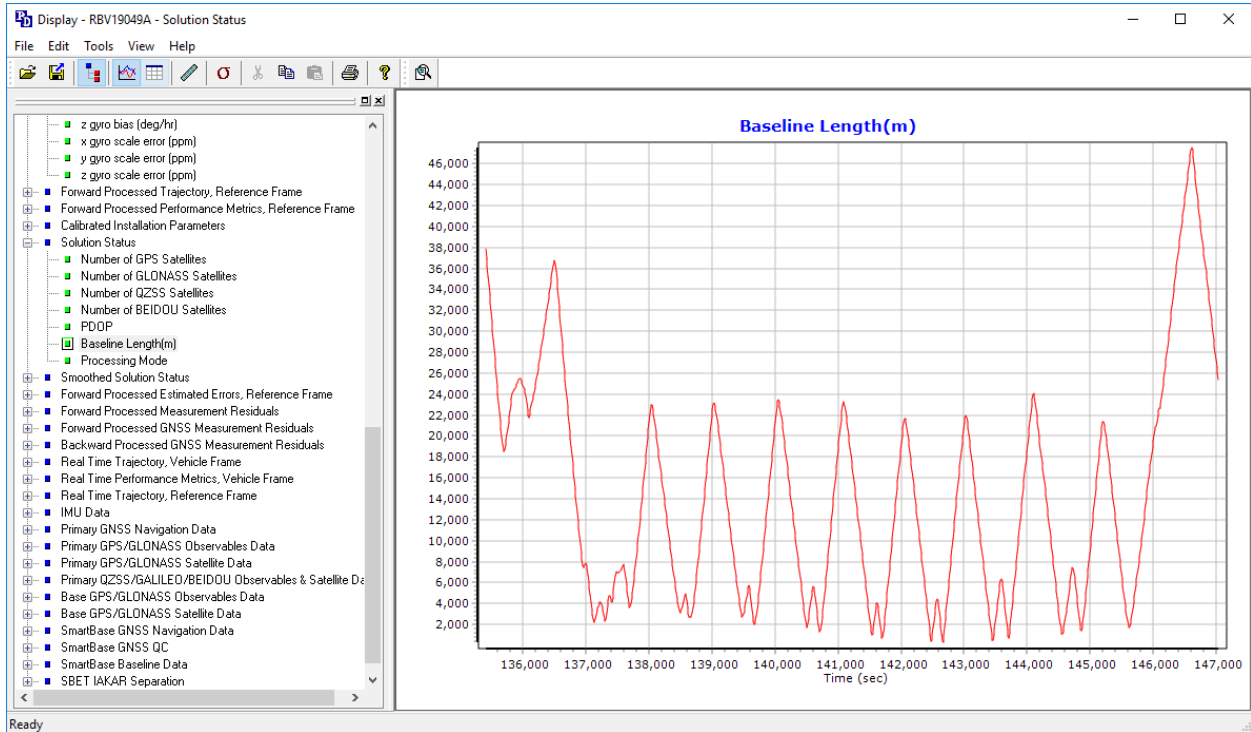
Standard Deviation: <3cm 10cm 50cm 1m 10m

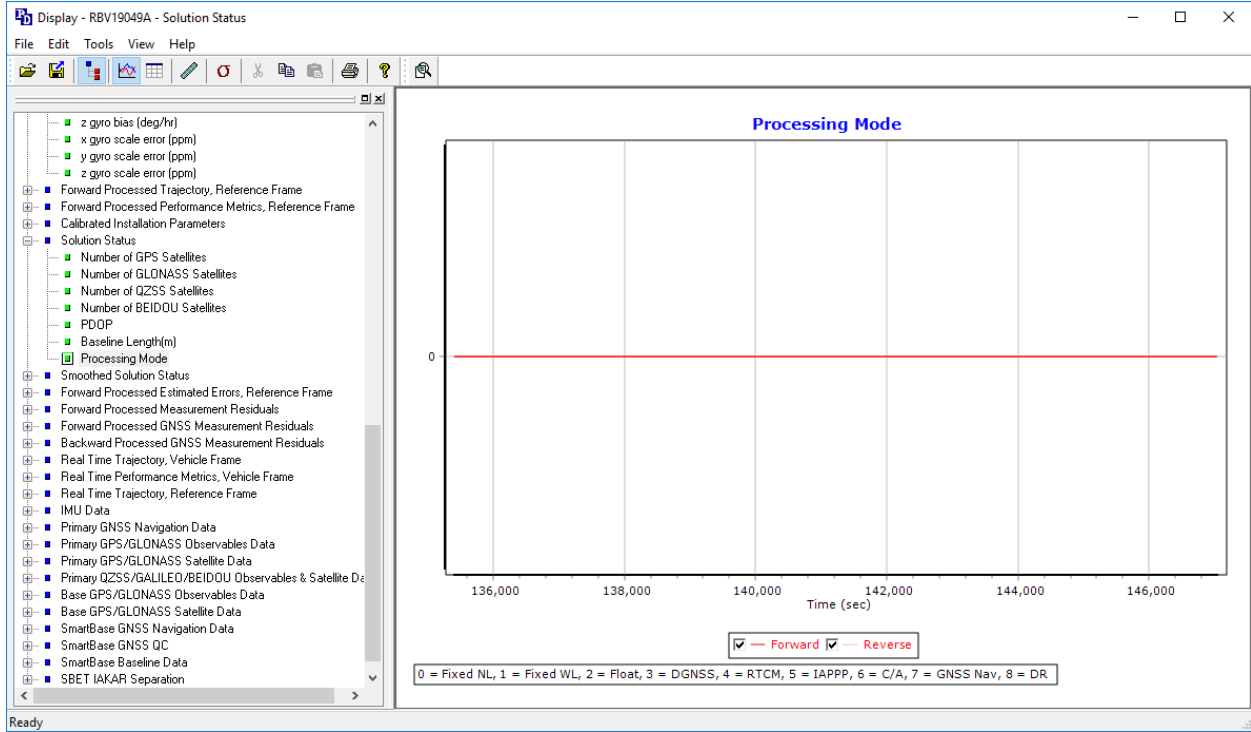
OK Cancel



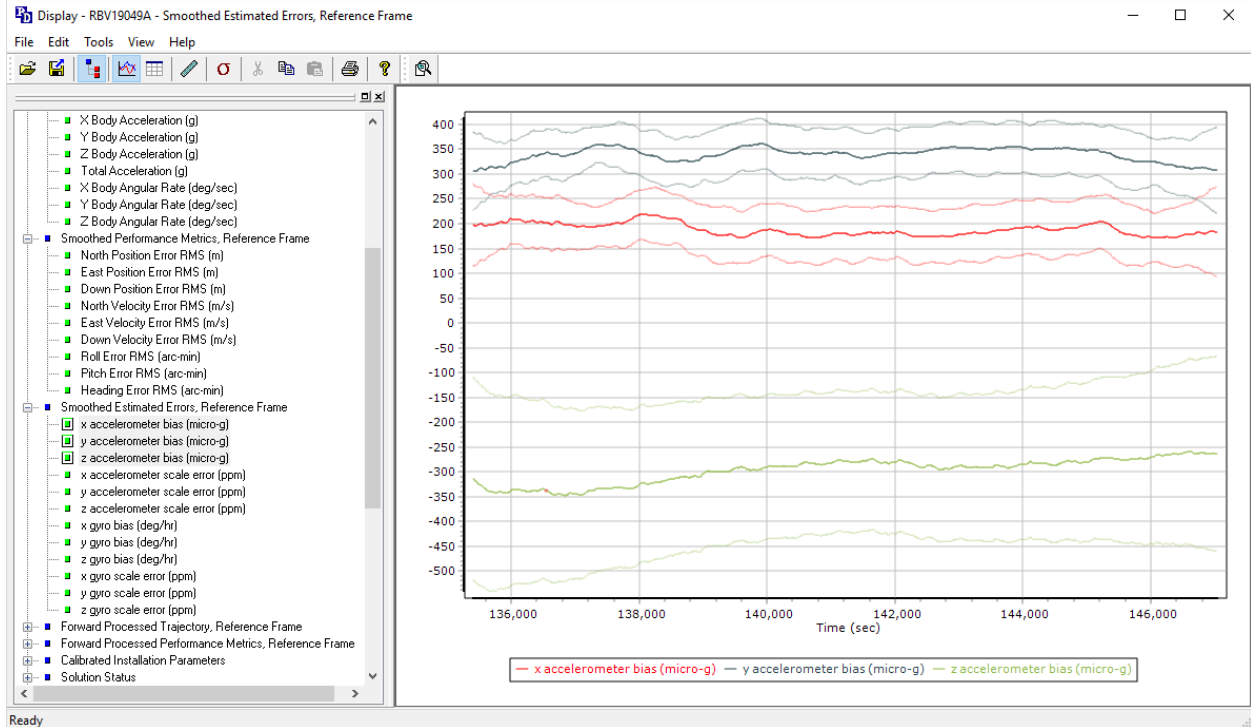


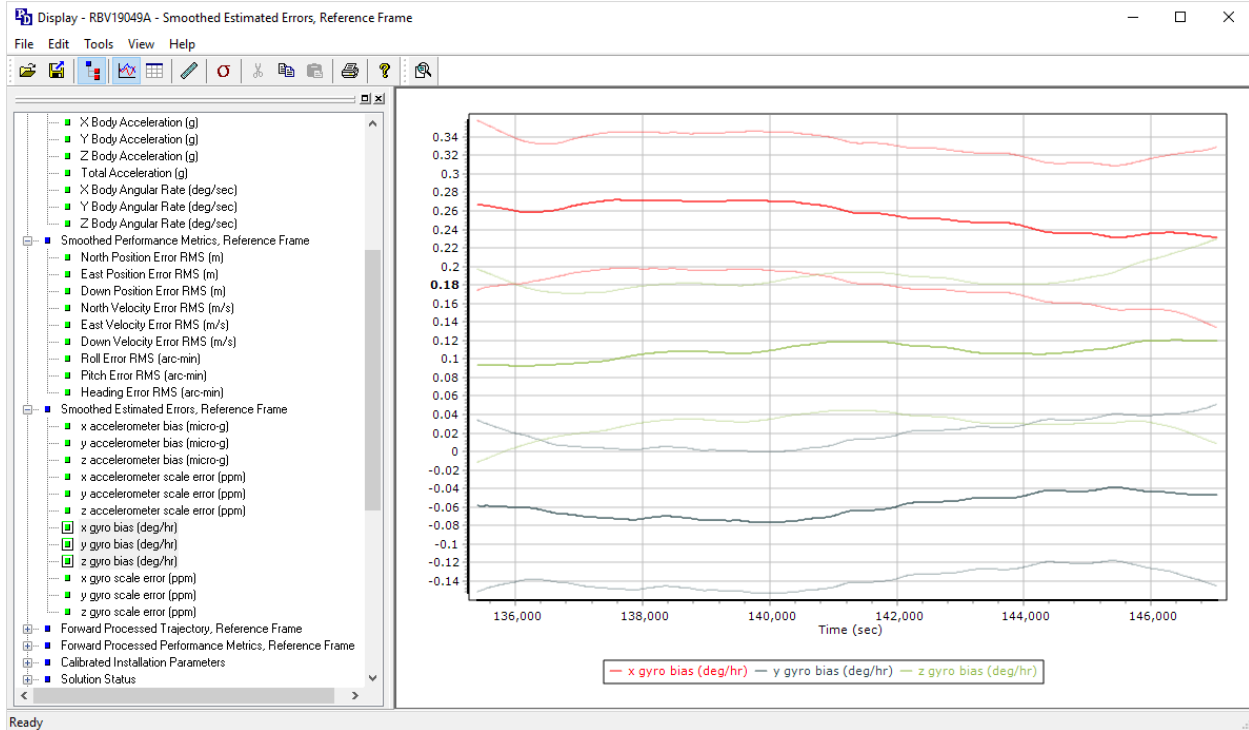
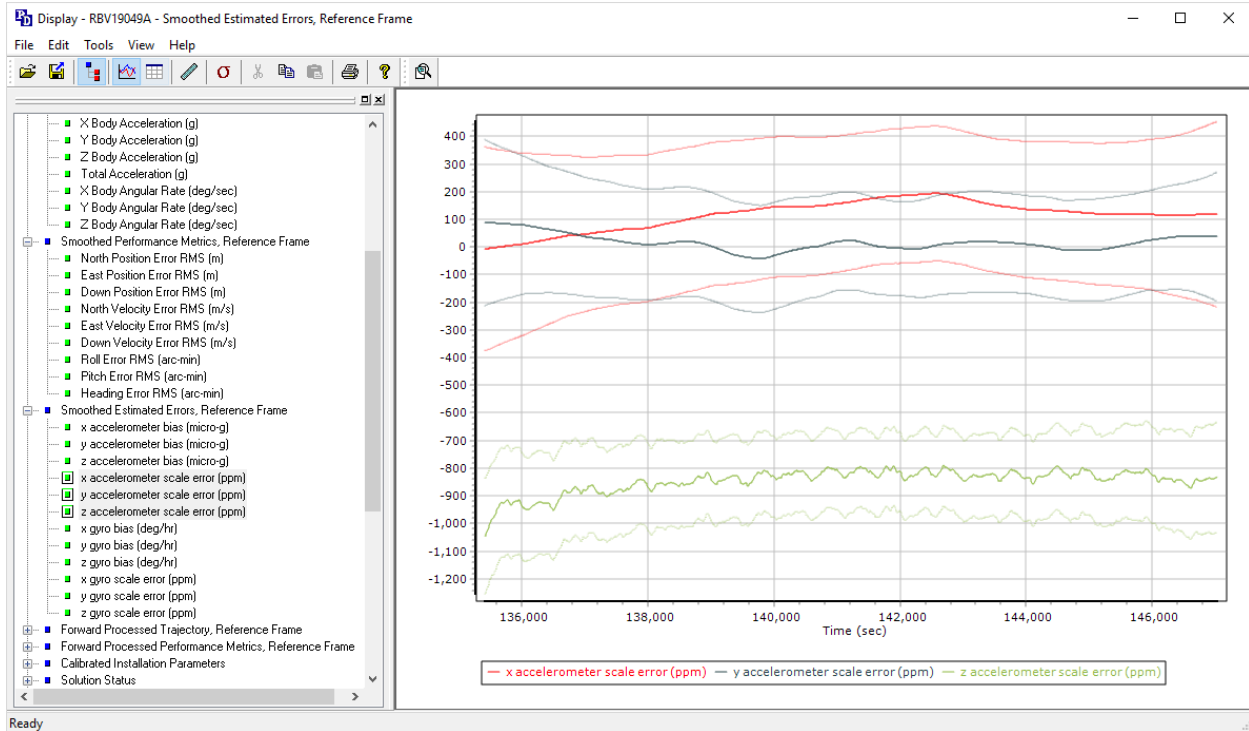


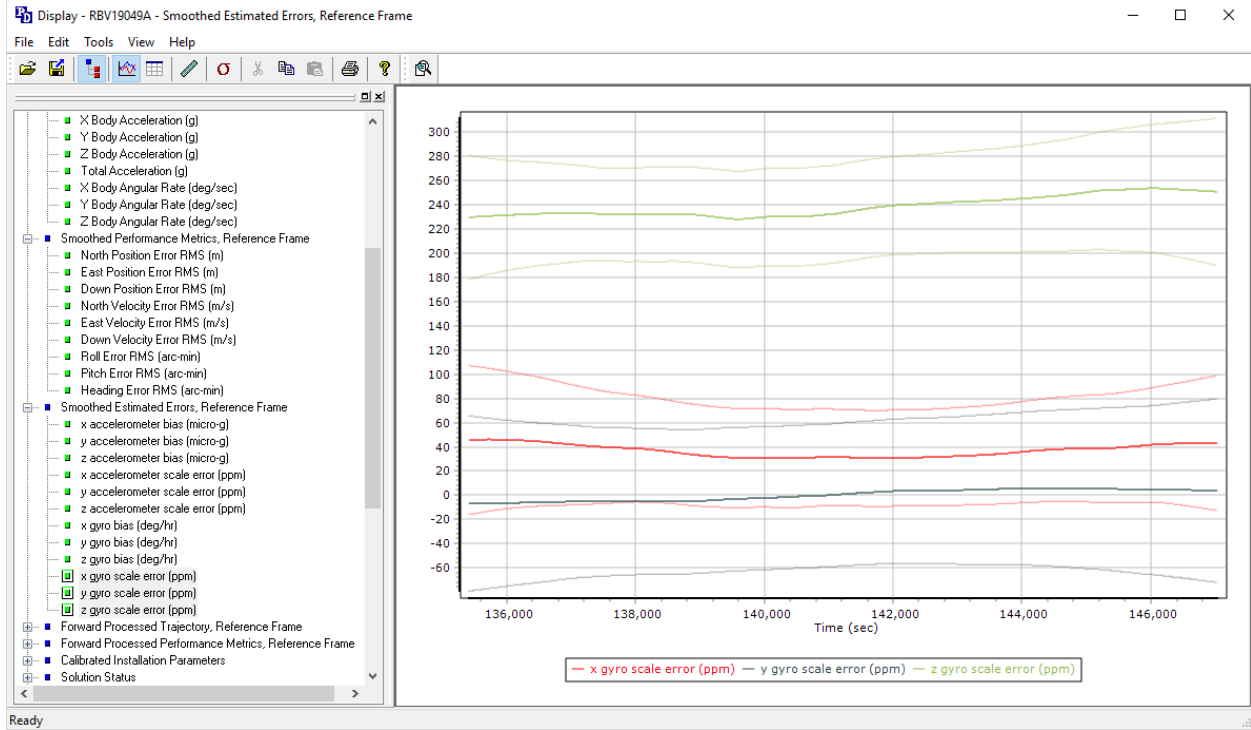




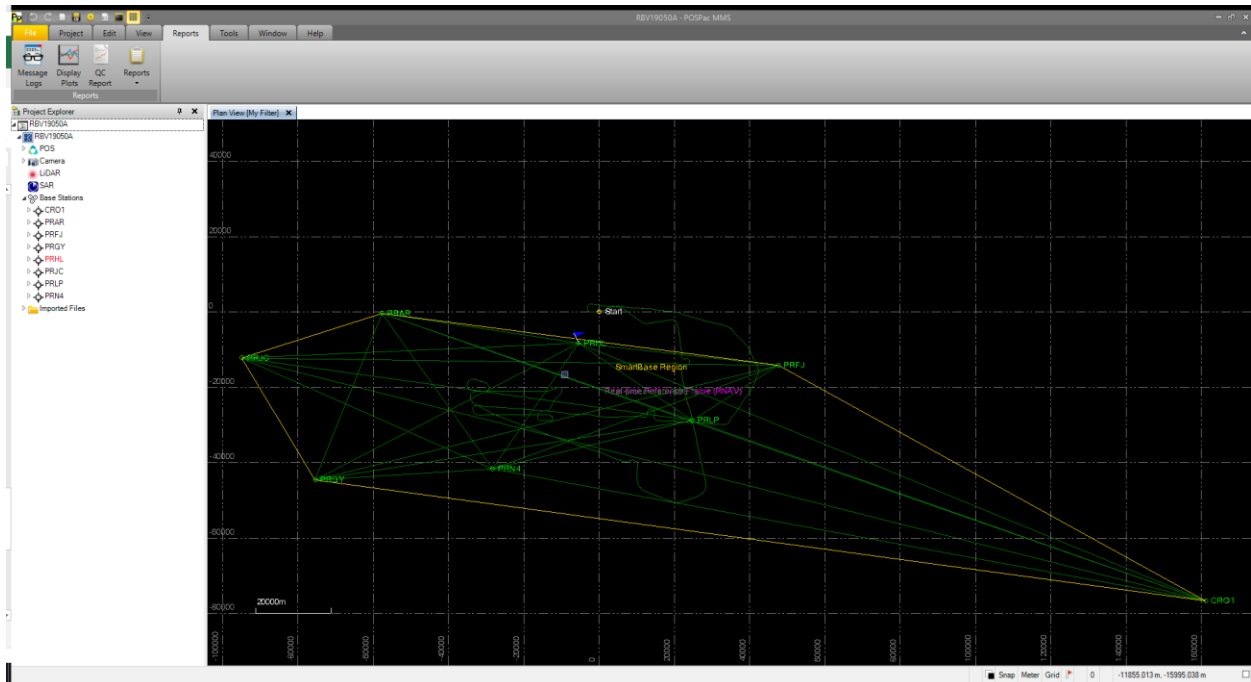
Sensor Errors

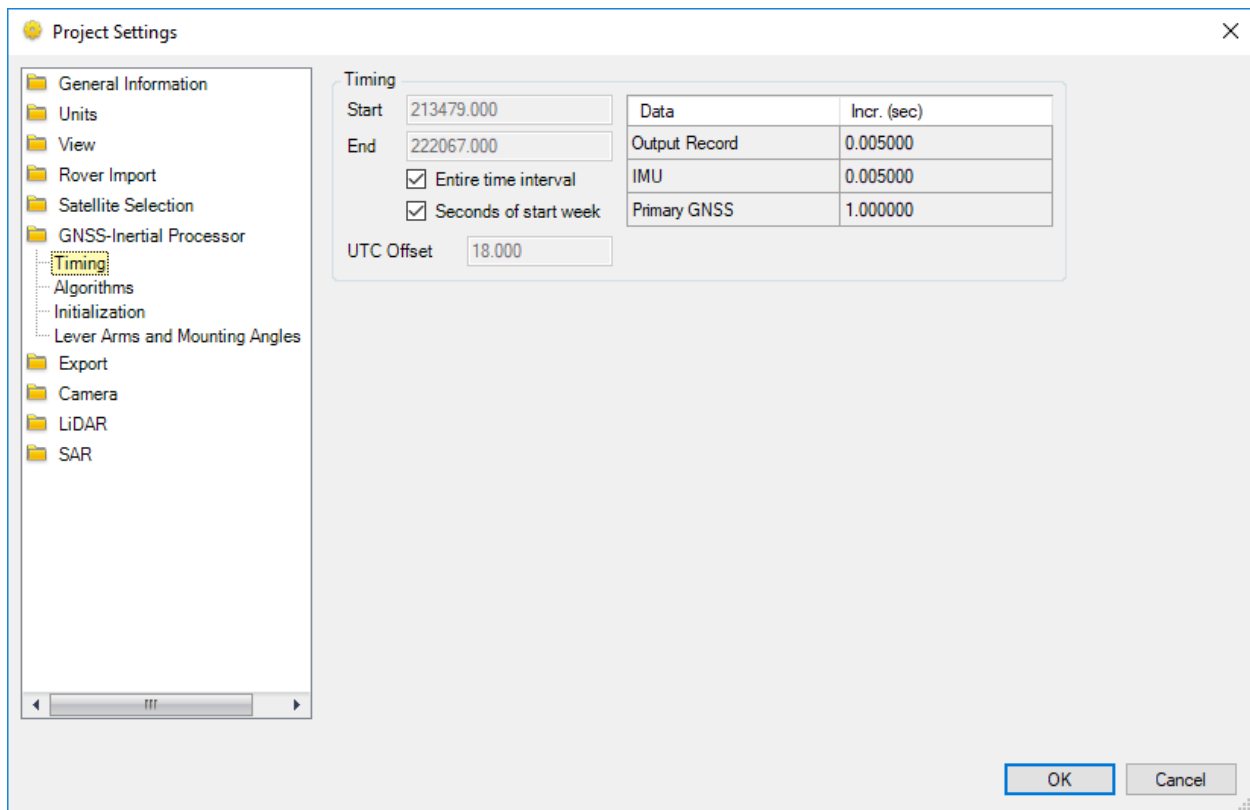
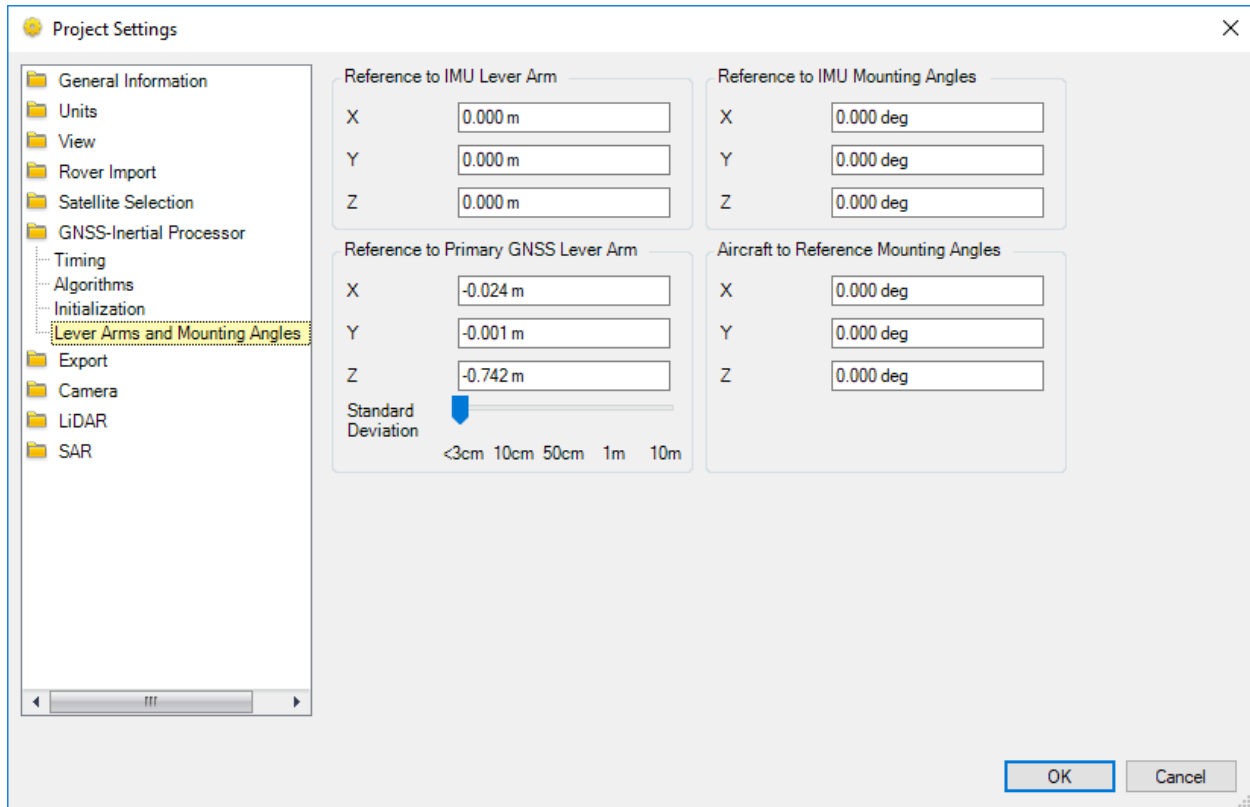


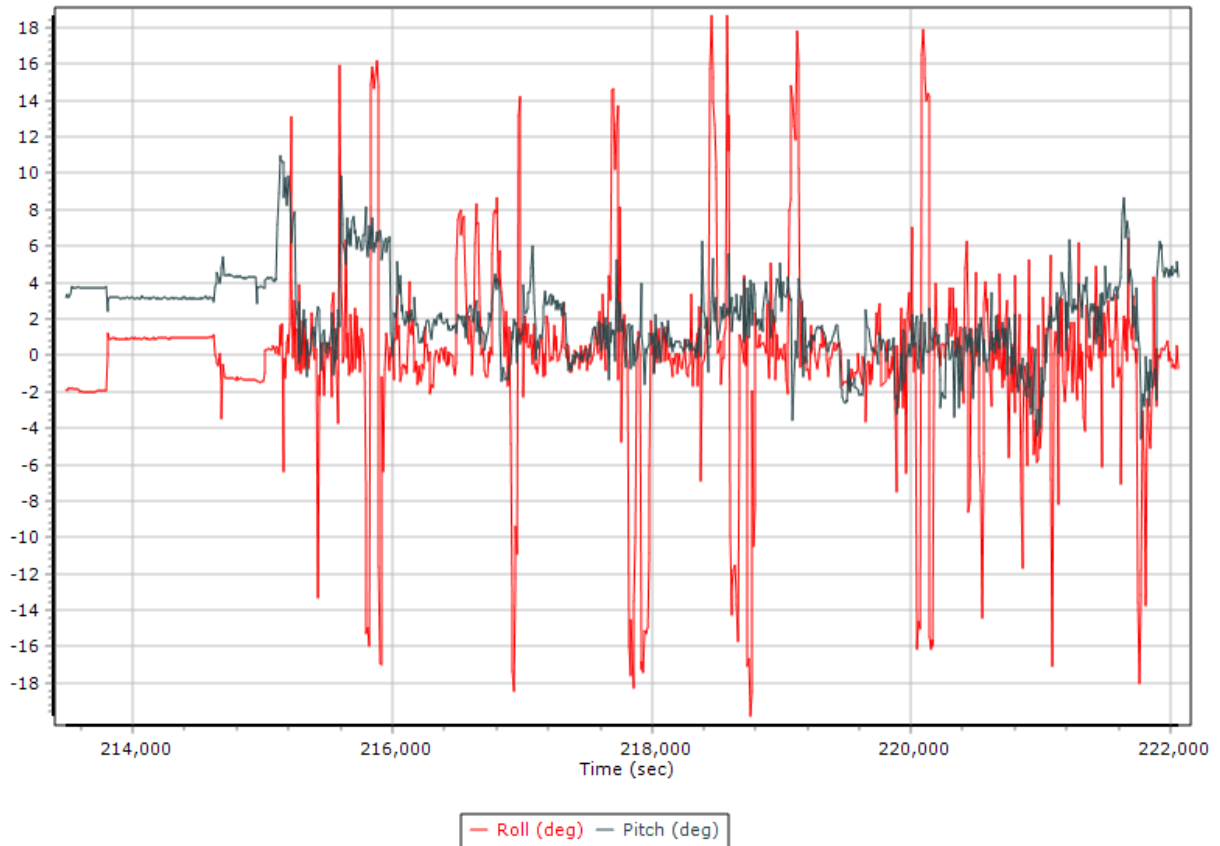
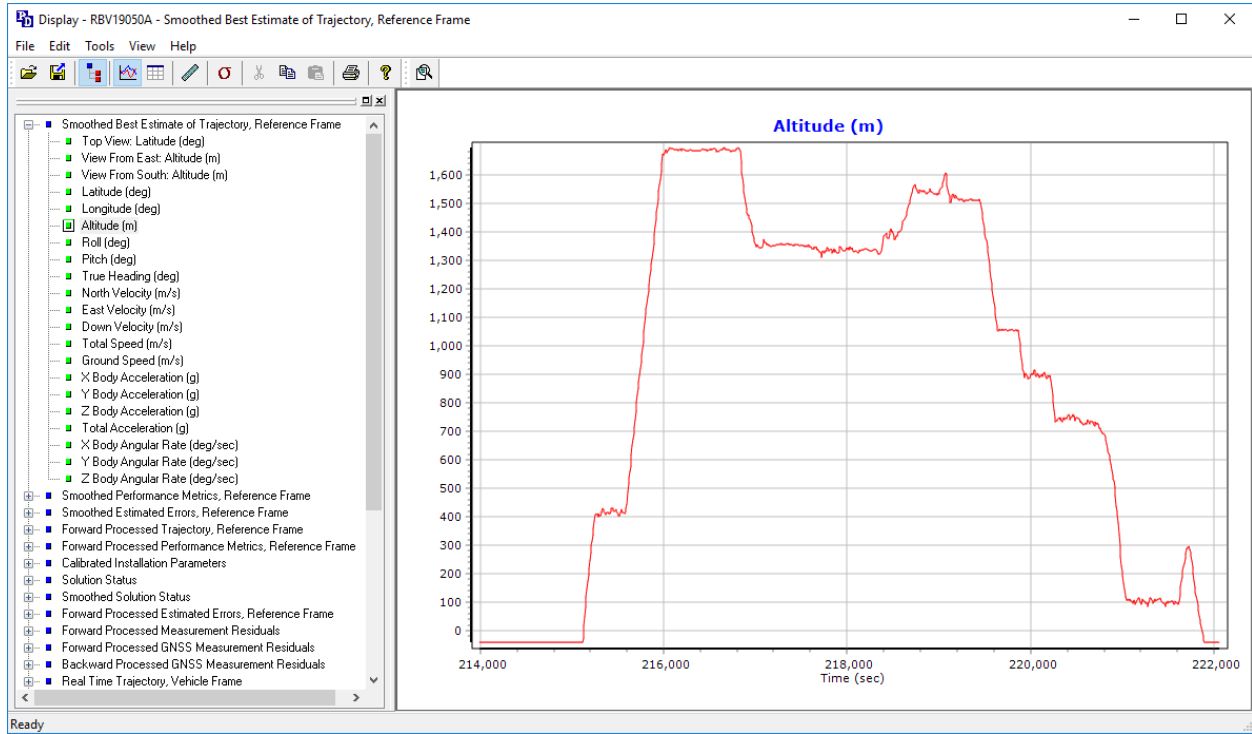


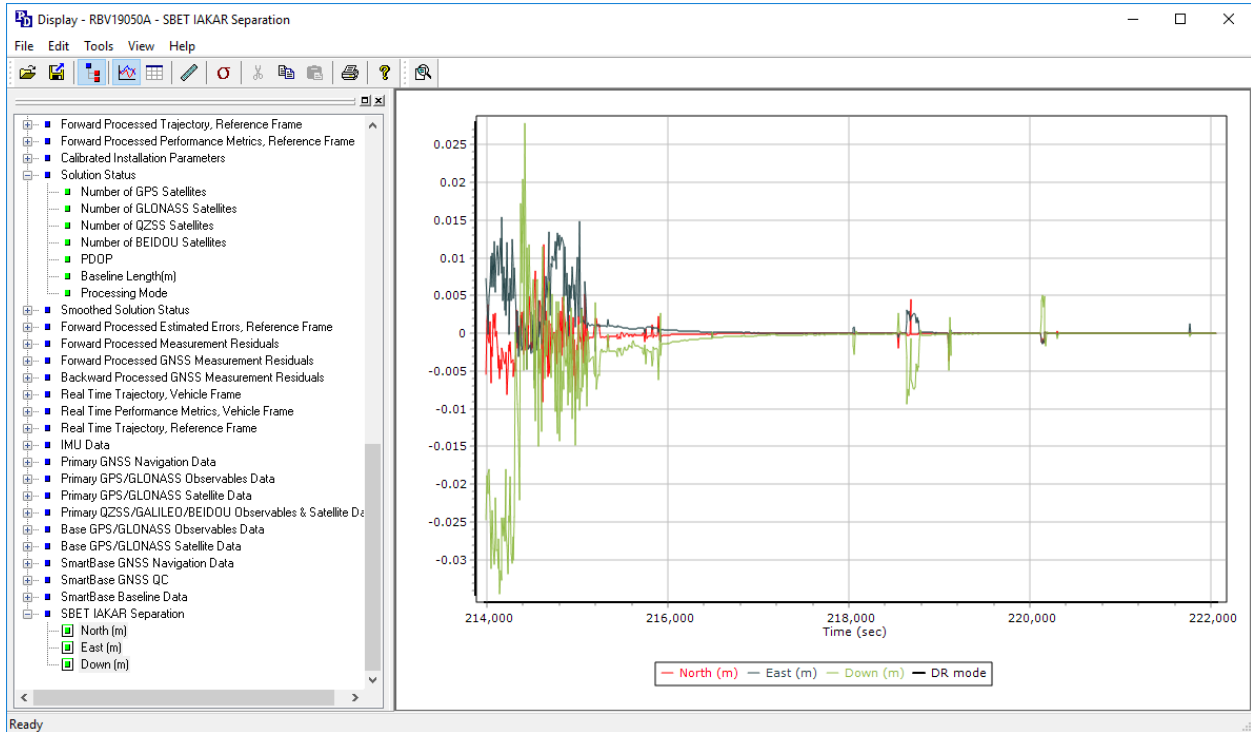


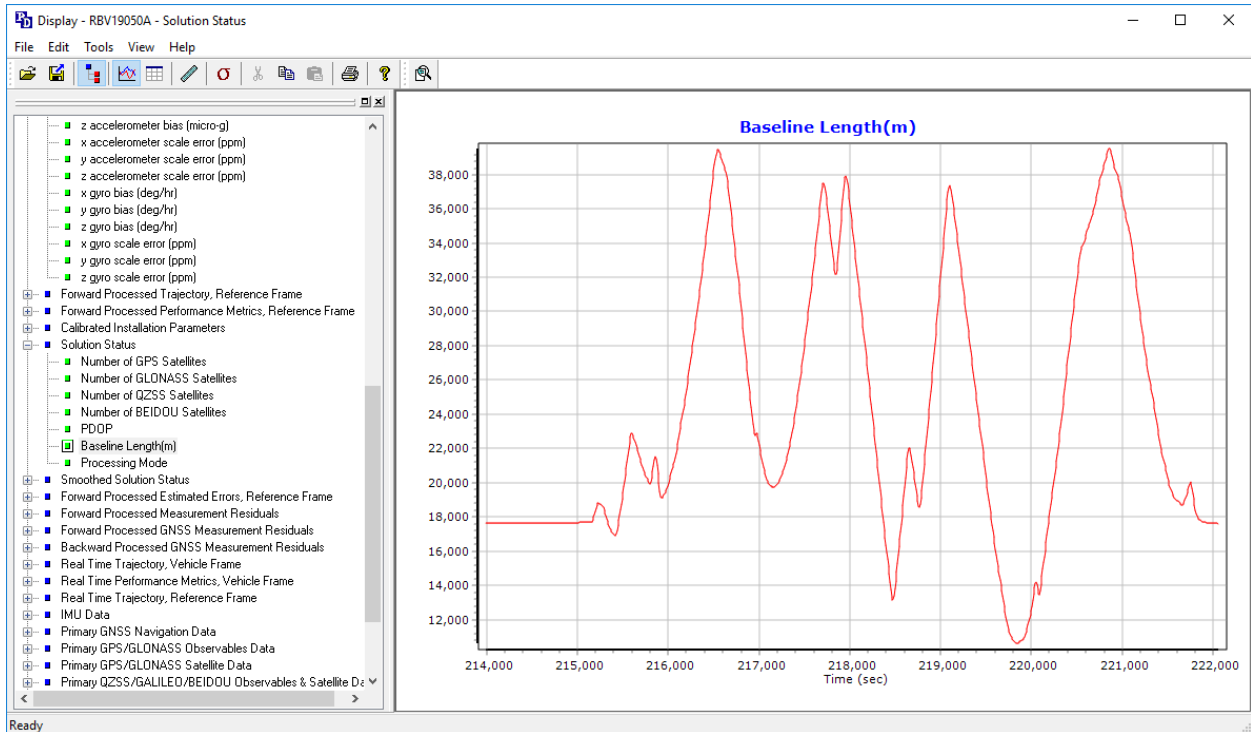
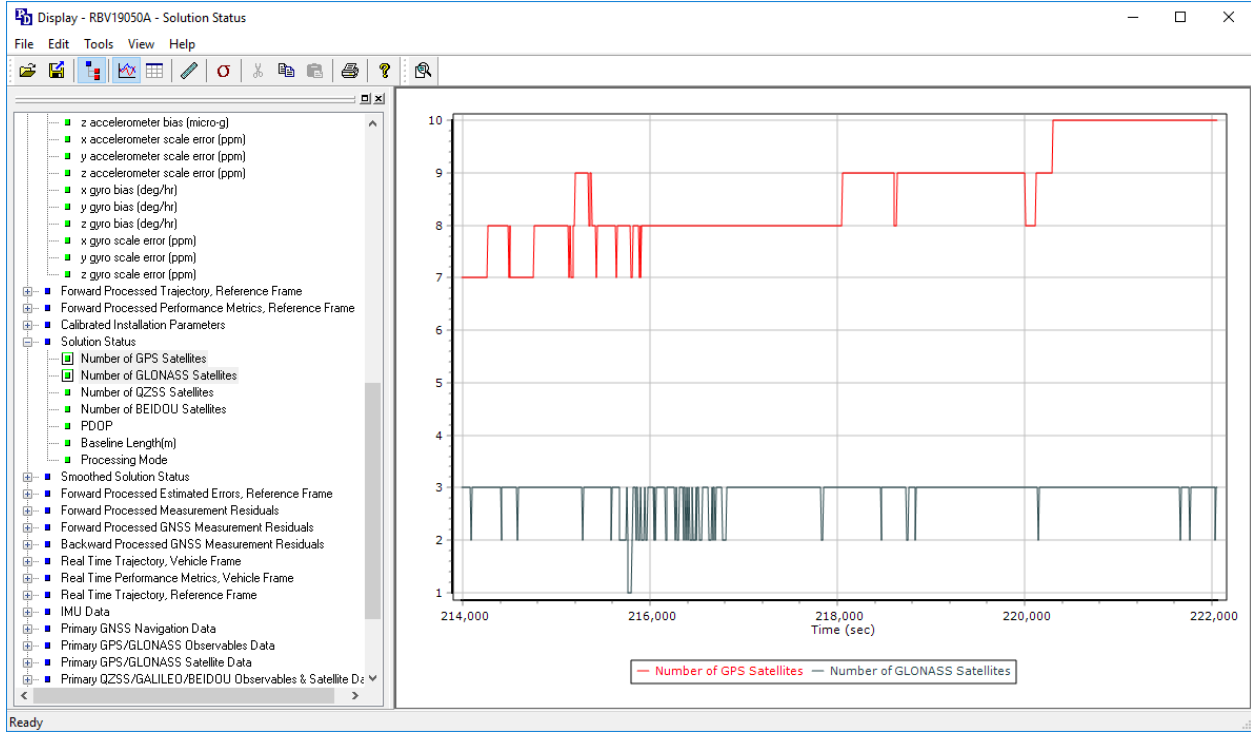
RBV19050A

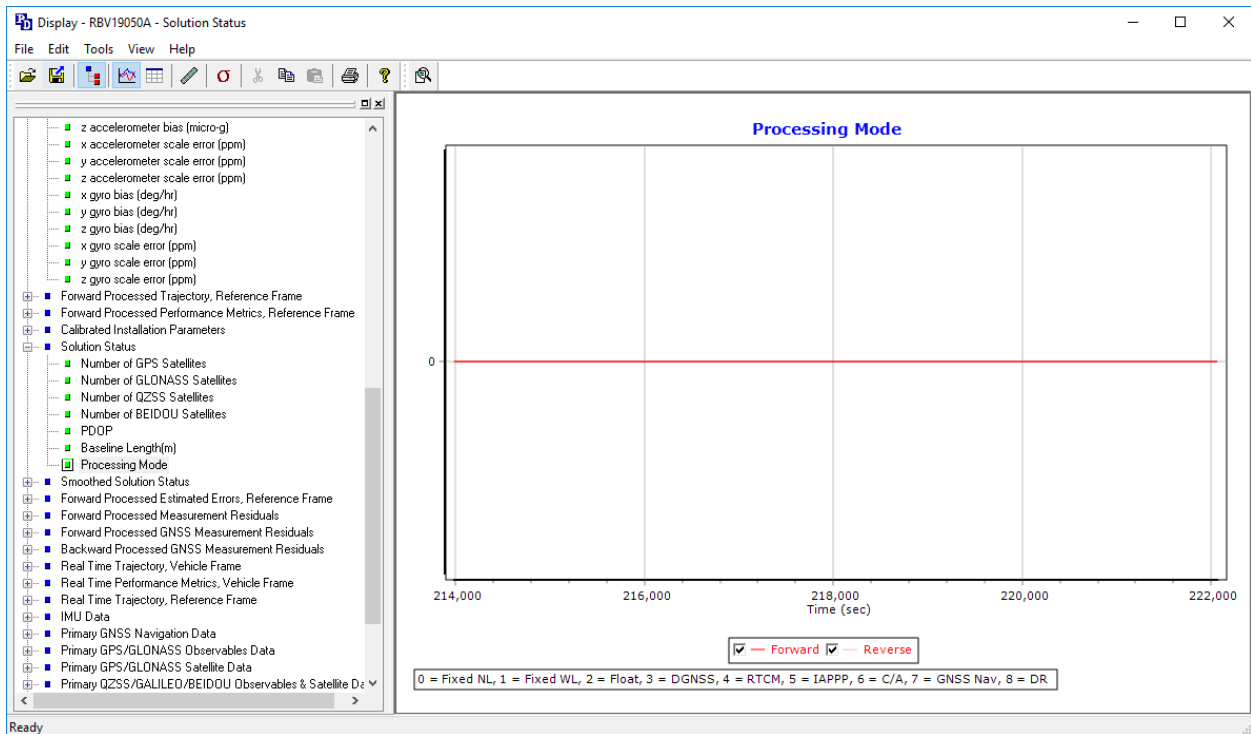
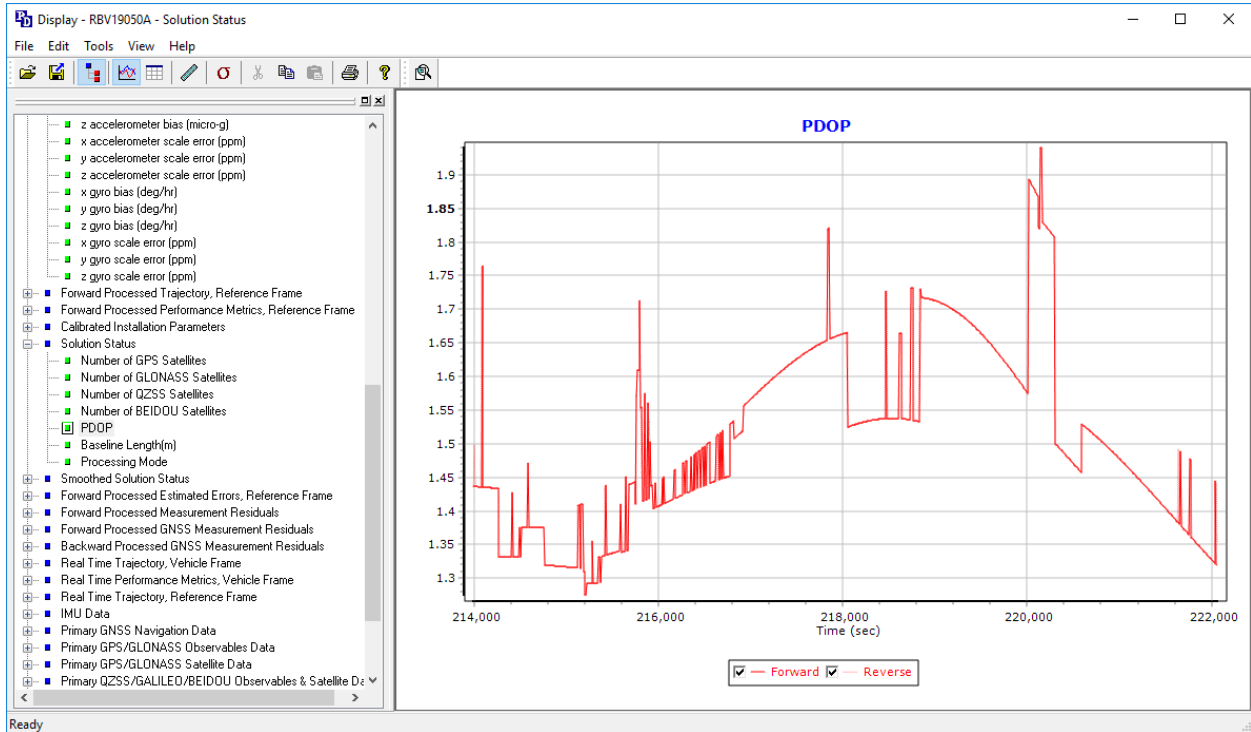




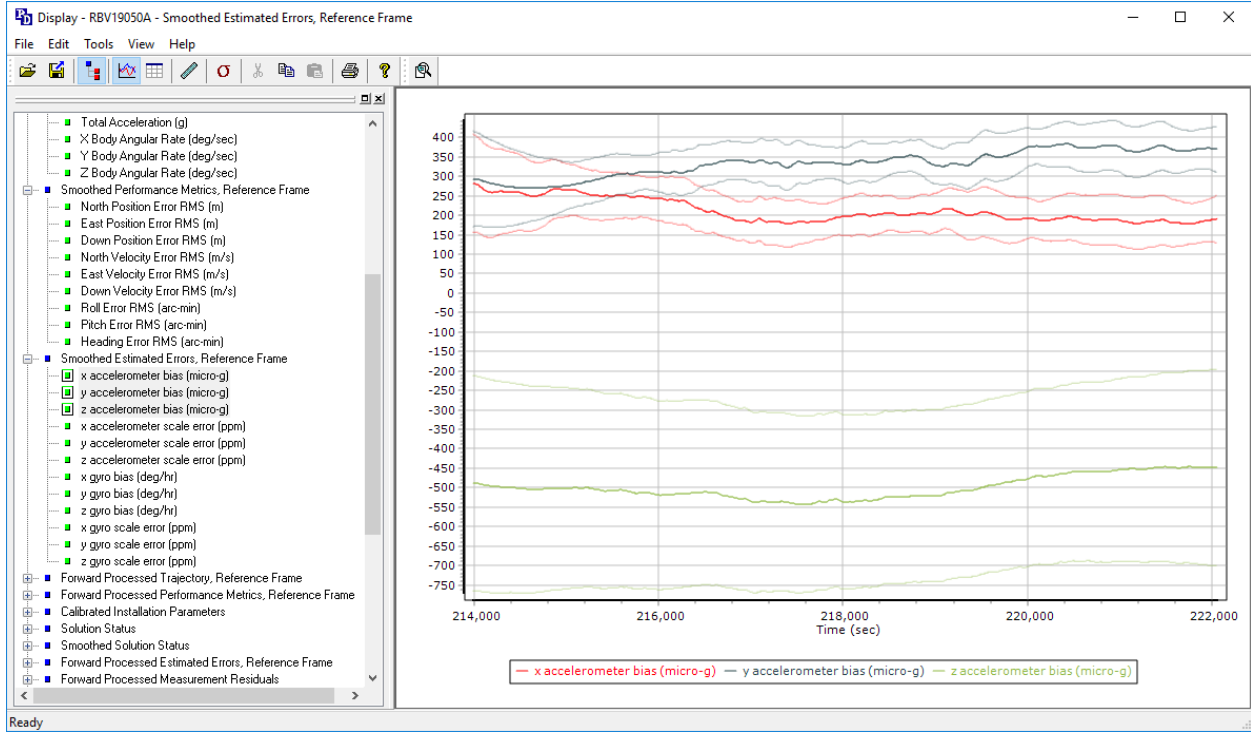


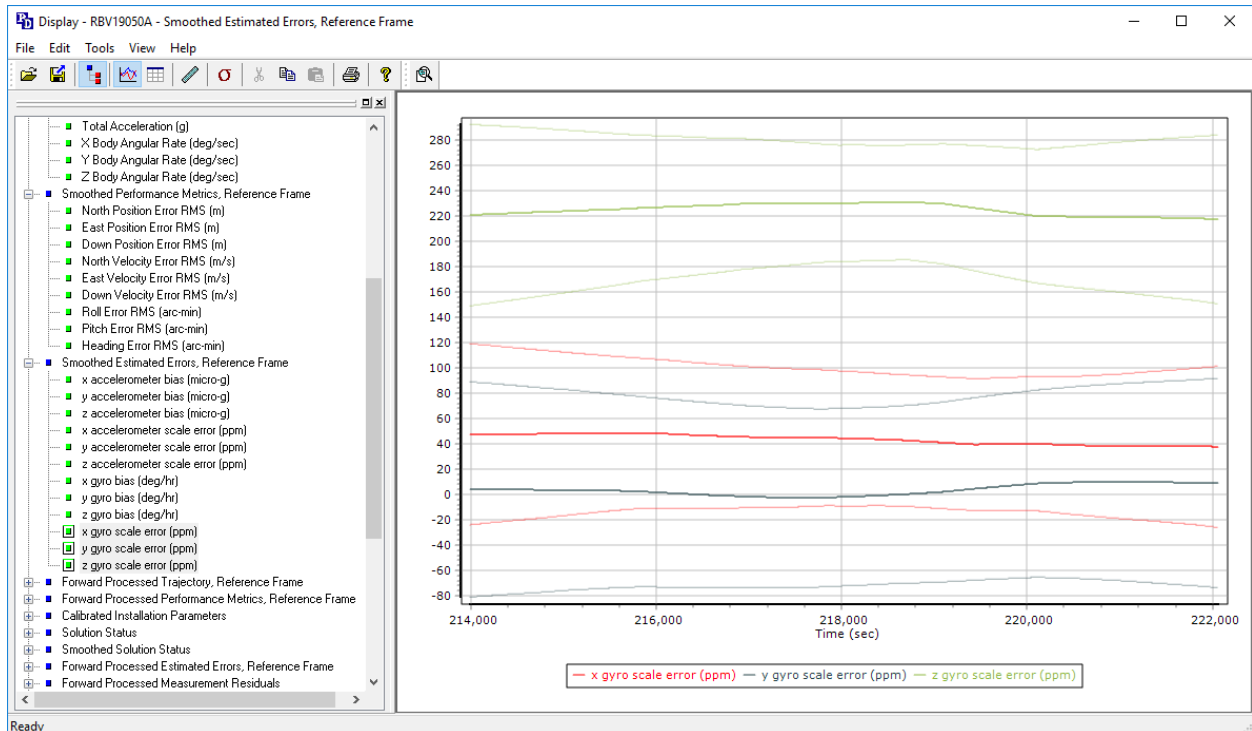
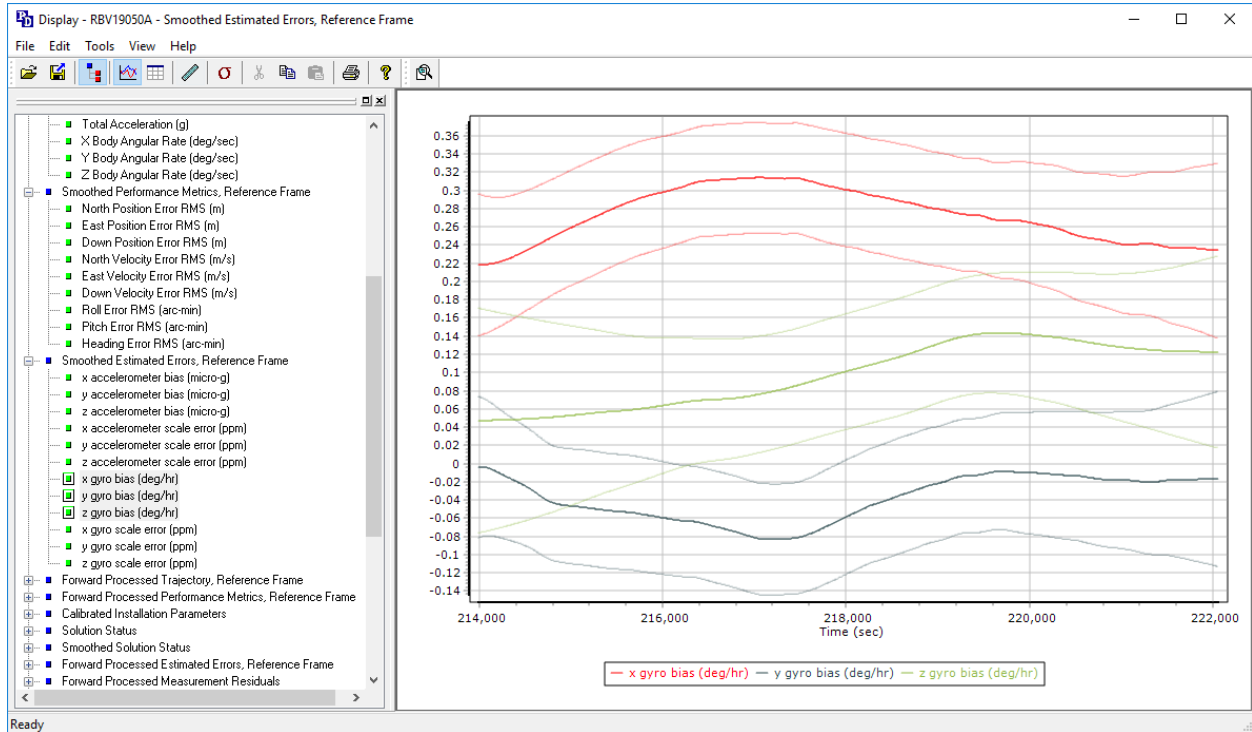




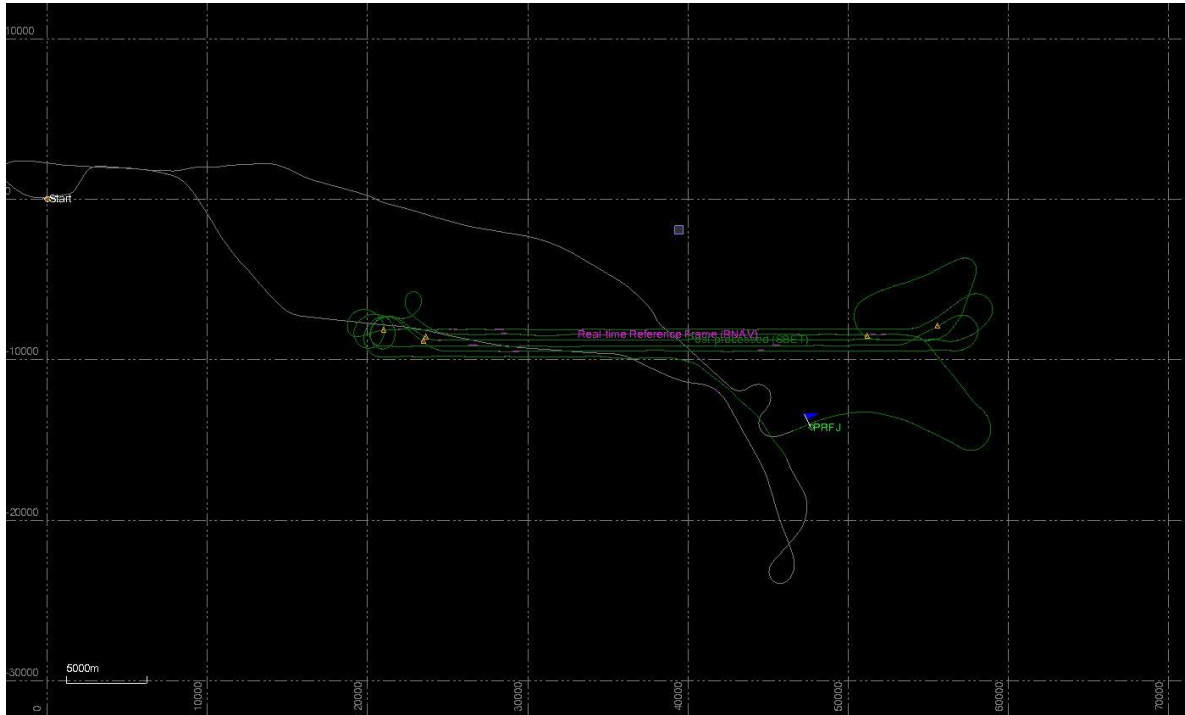


Sensor Errors





RBV19063A



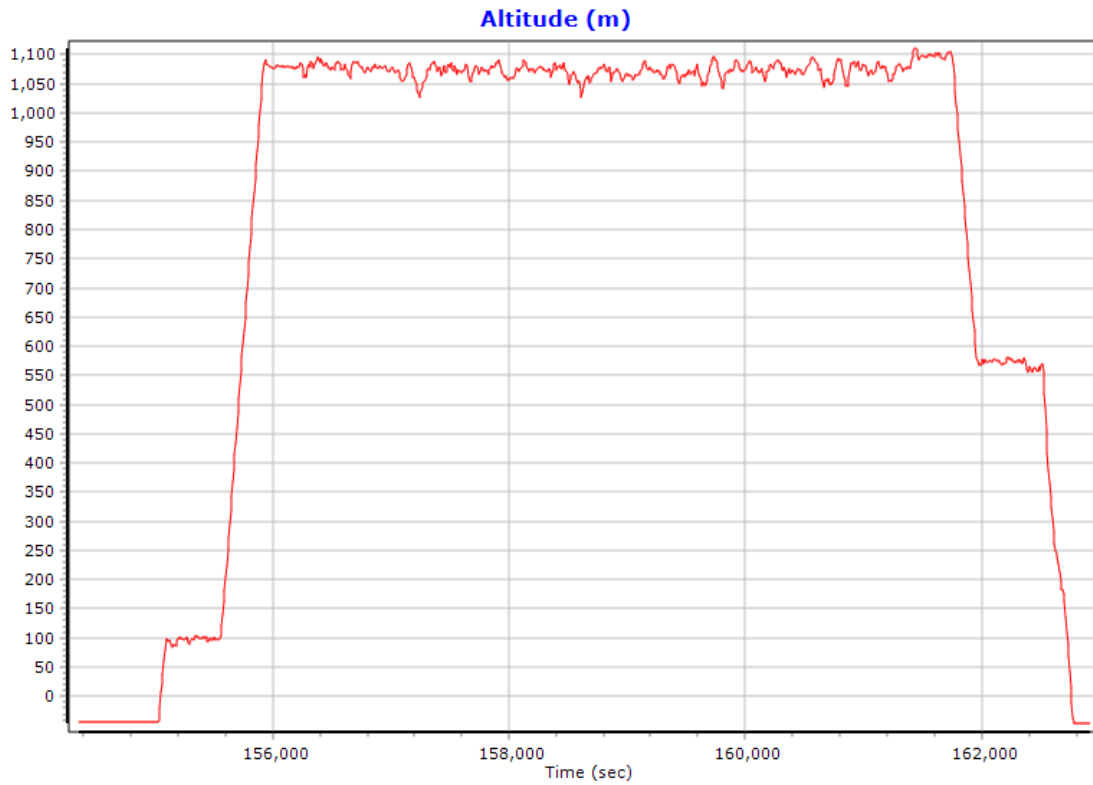
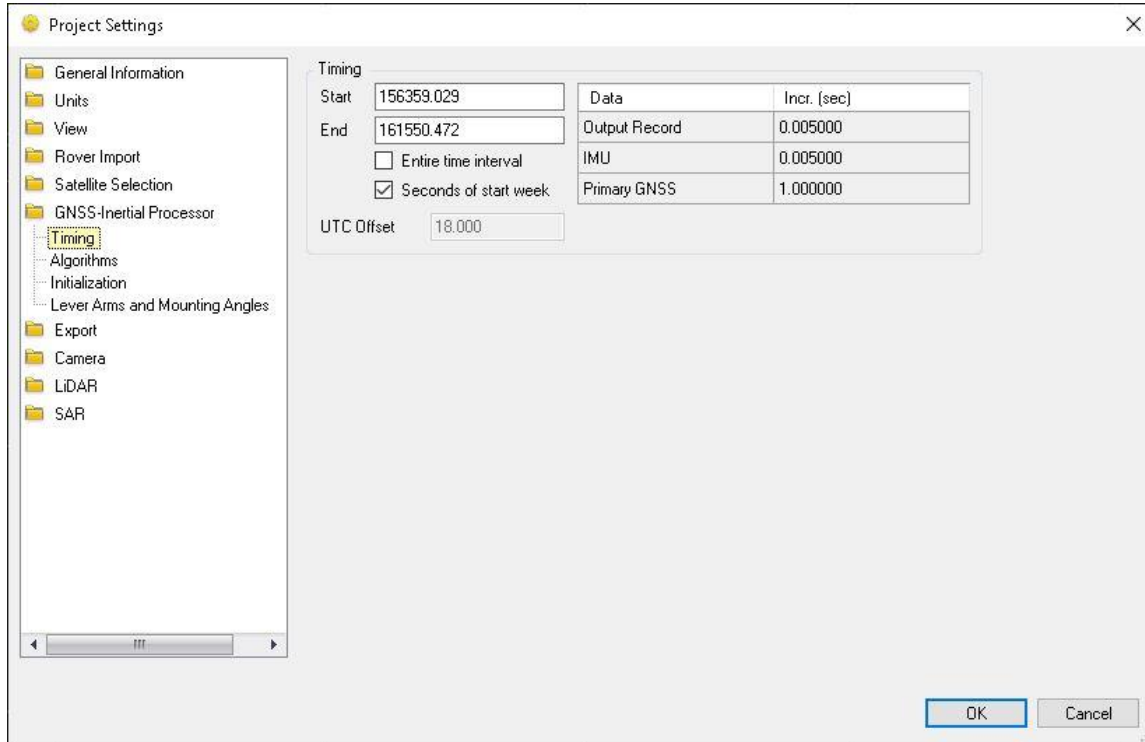
Project Settings

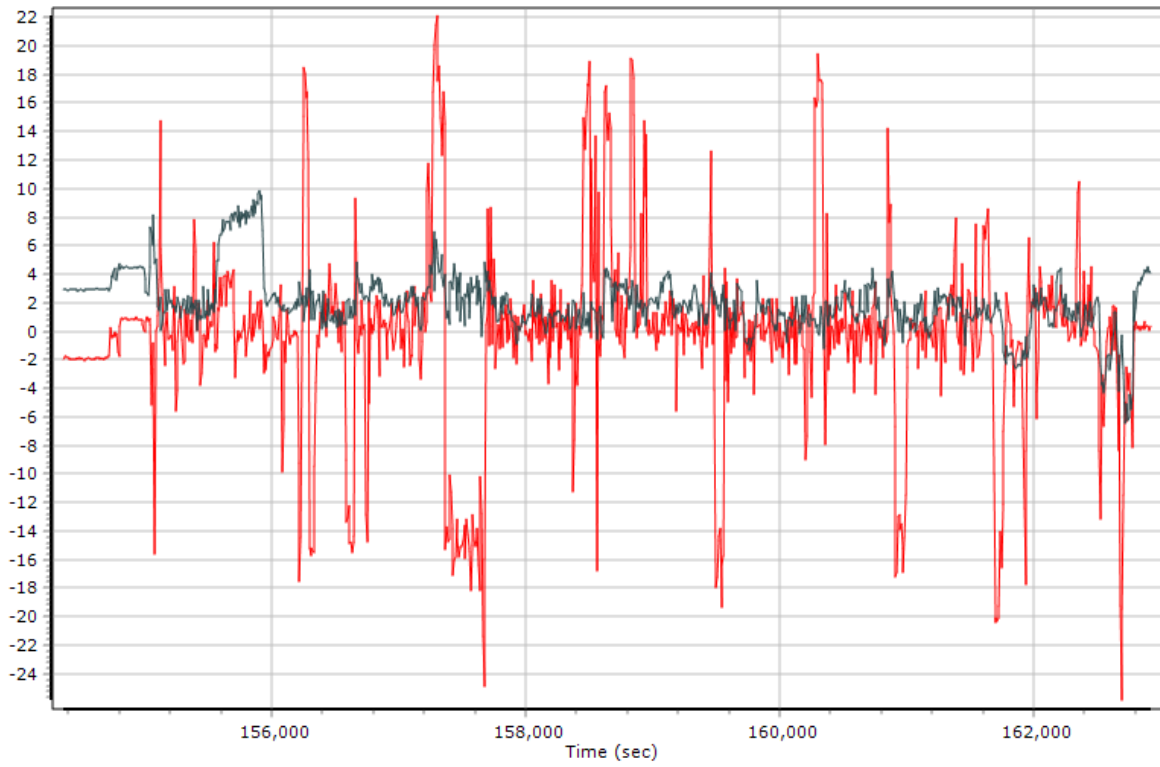
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LIDAR
- SAR

Reference to IMU Lever Arm	Reference to IMU Mounting Angles
X: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

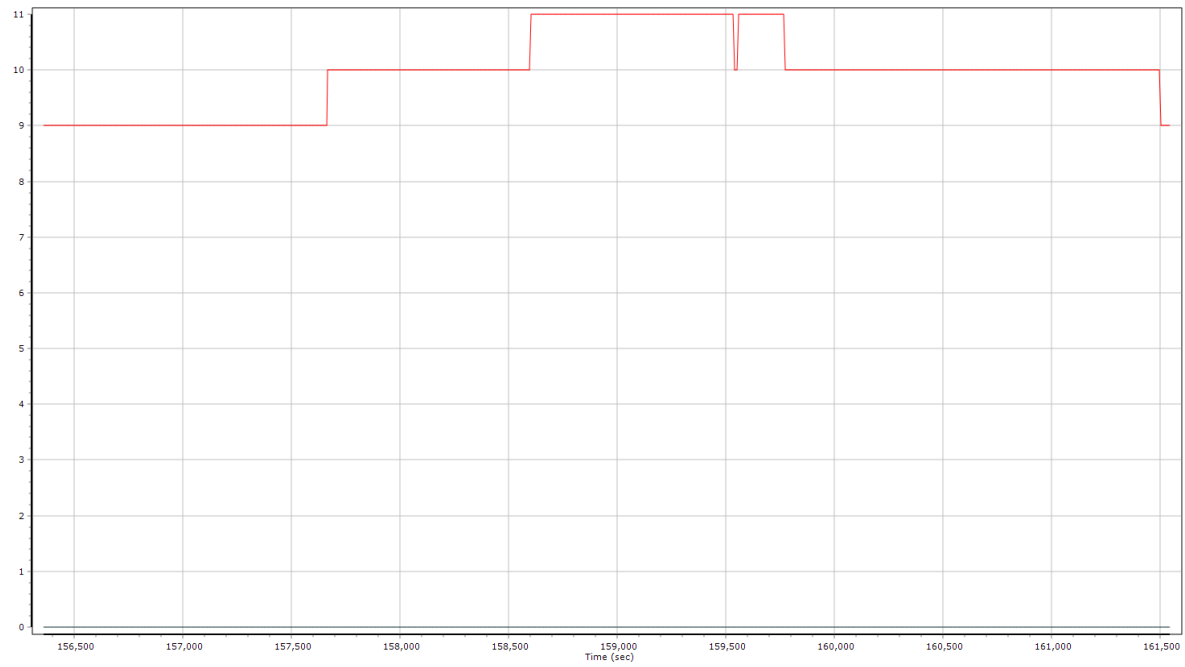
Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 m	Z: 0.000 deg

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

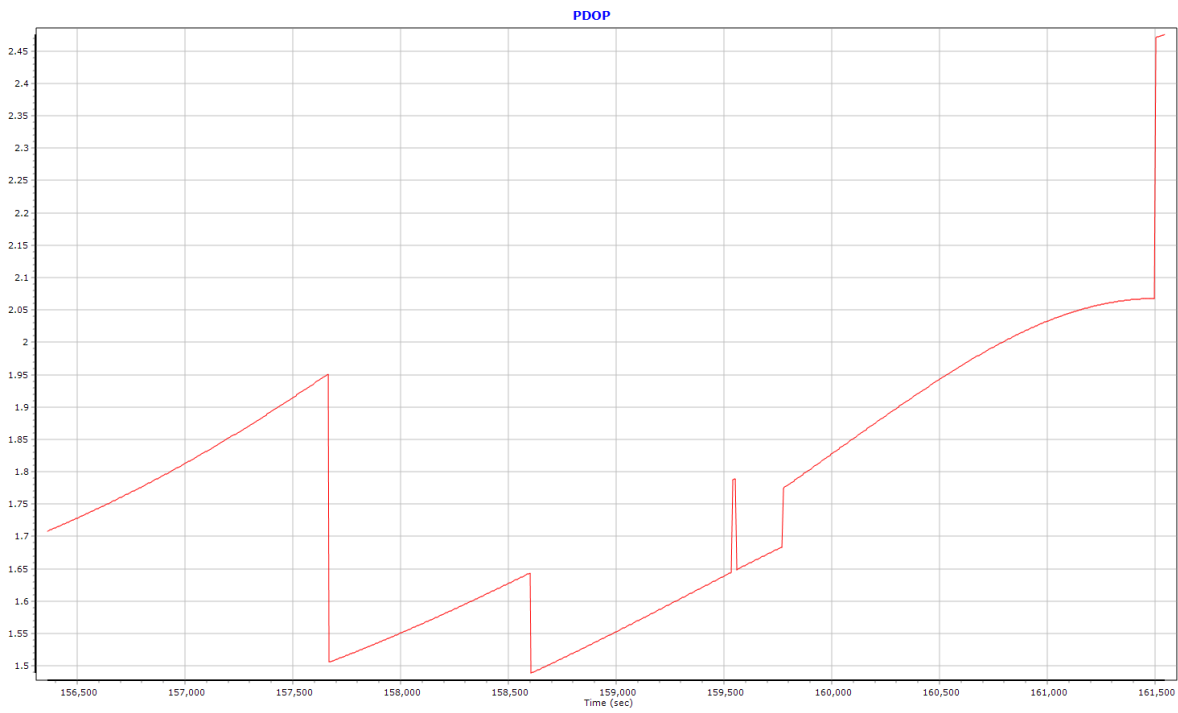
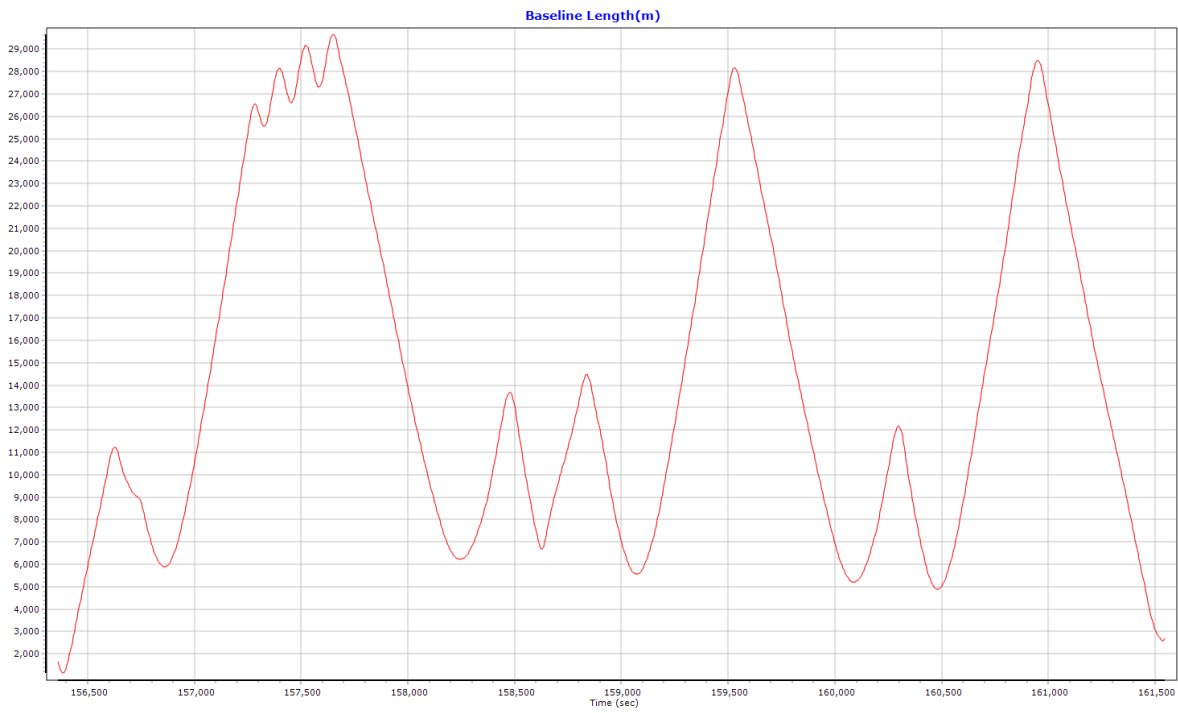


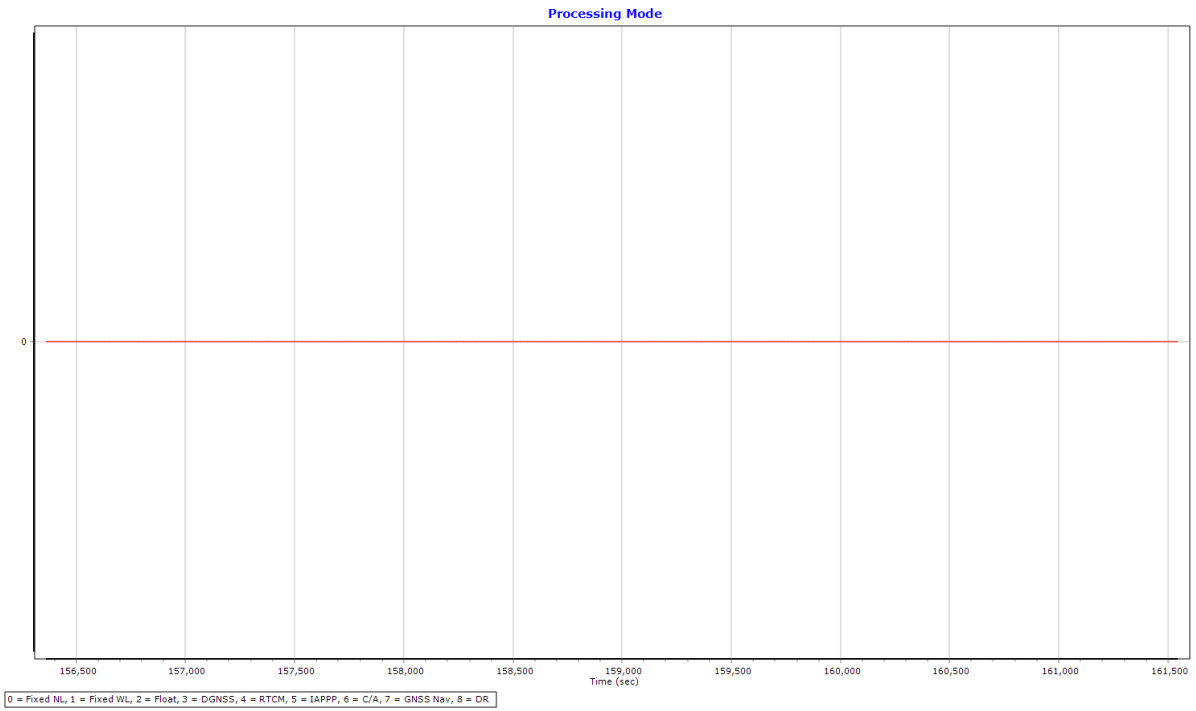


— Roll (deg) — Pitch (deg)

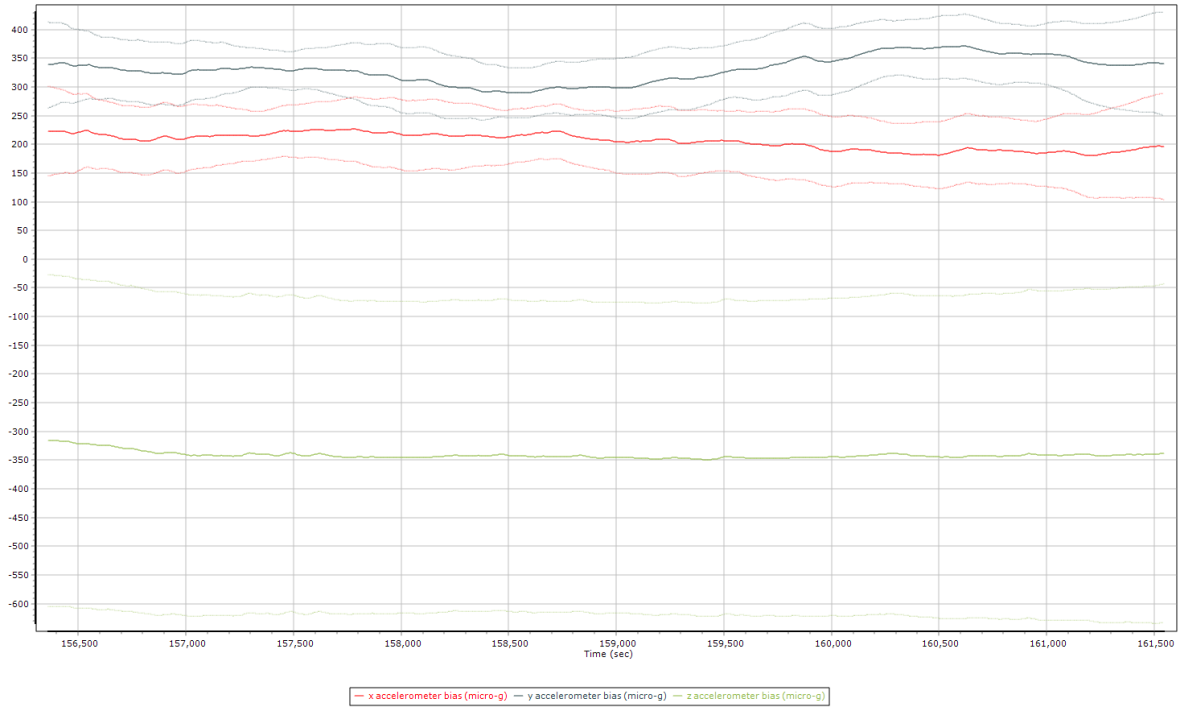


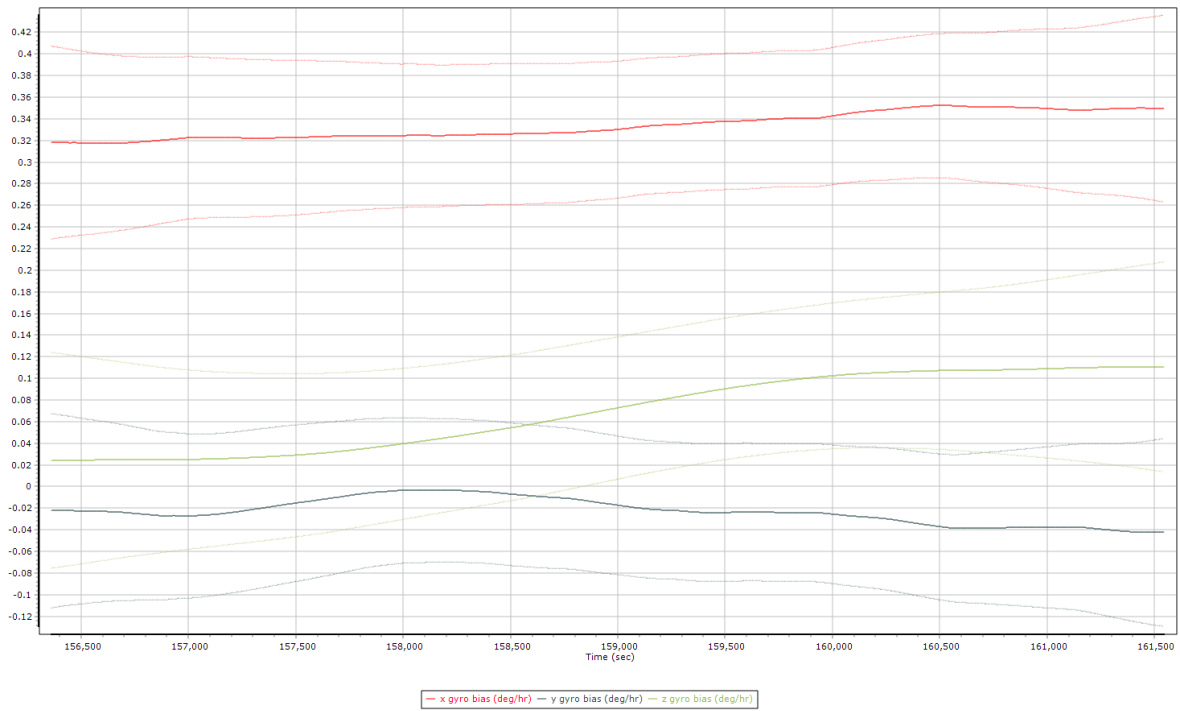
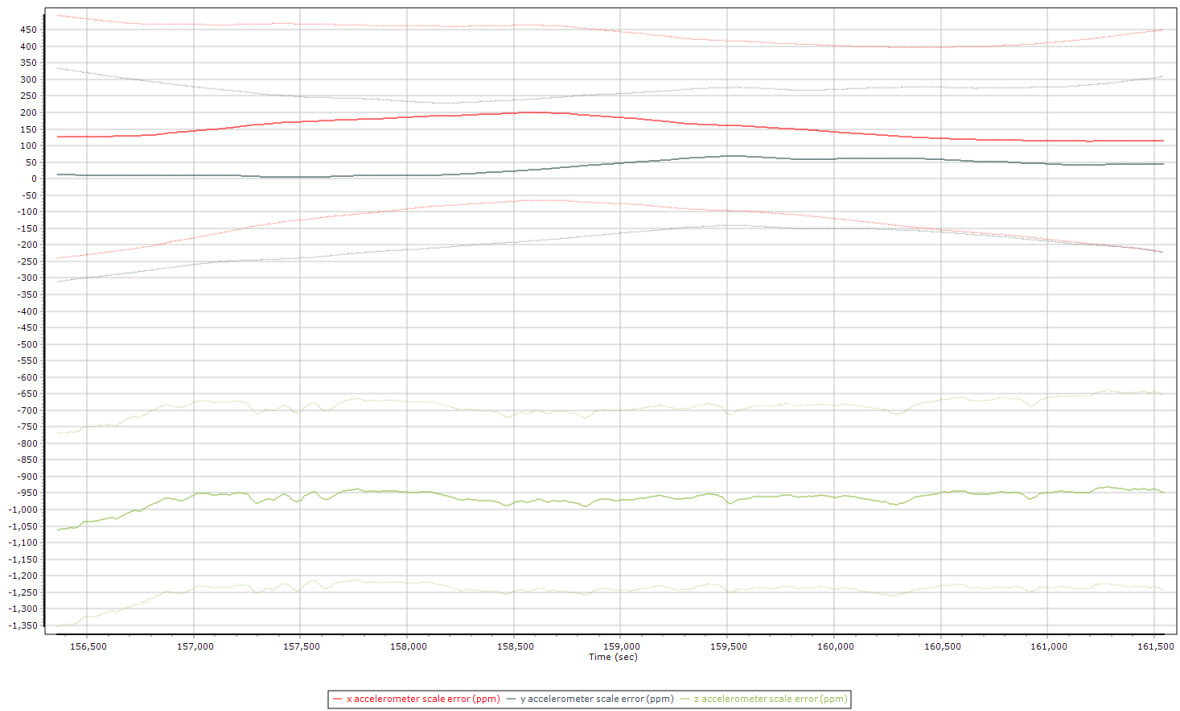
— Number of GPS Satellites — Number of GLONASS Satellites

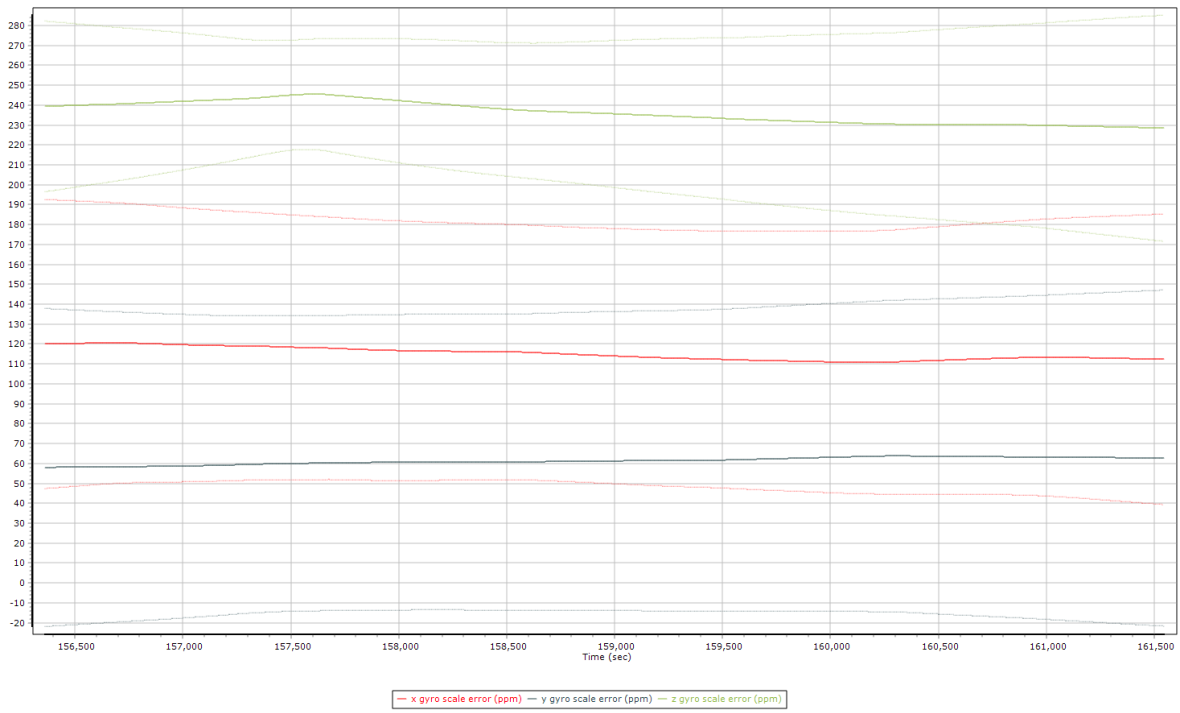




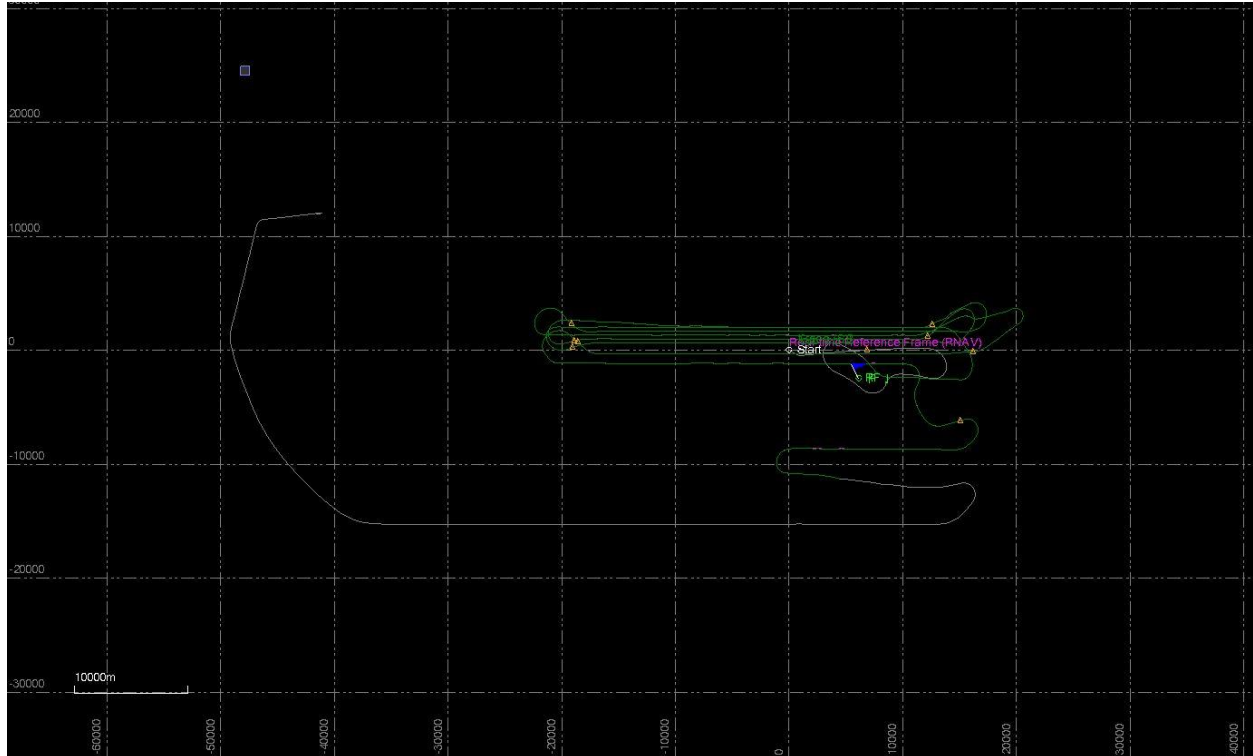
Sensor Errors

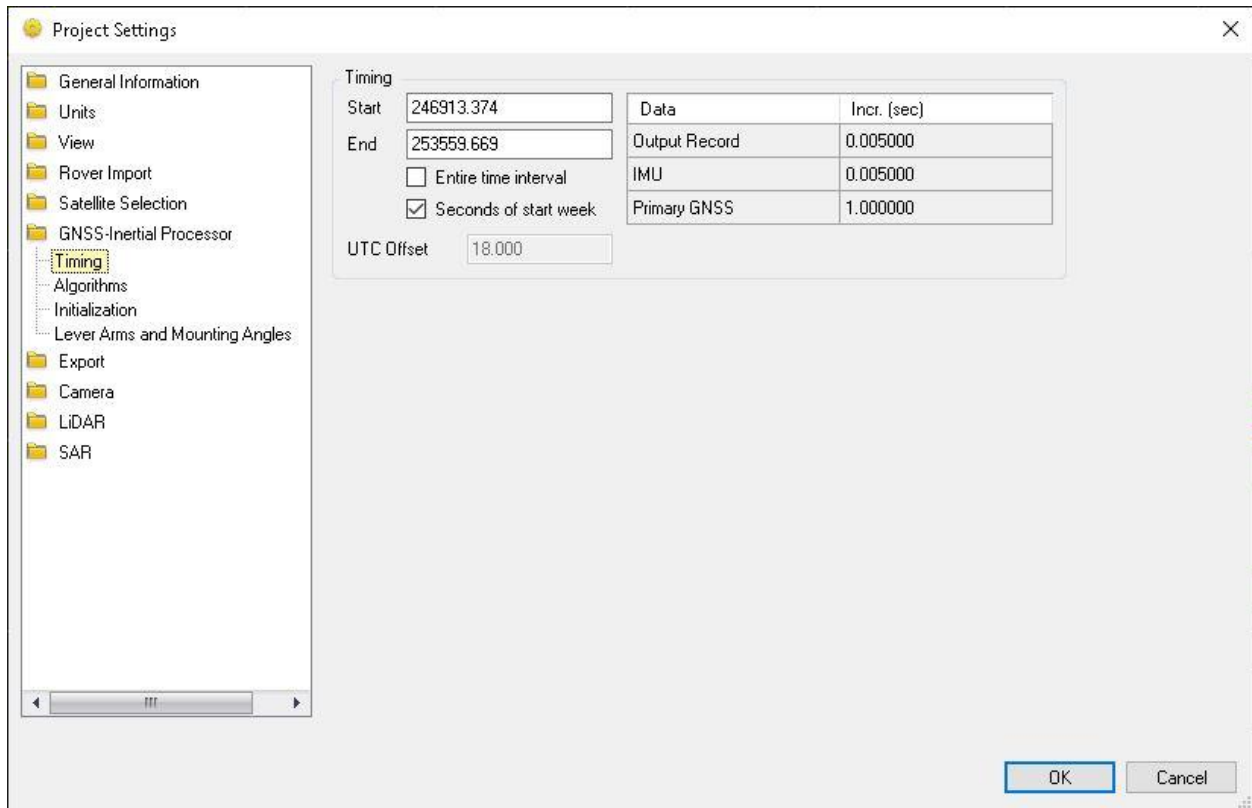
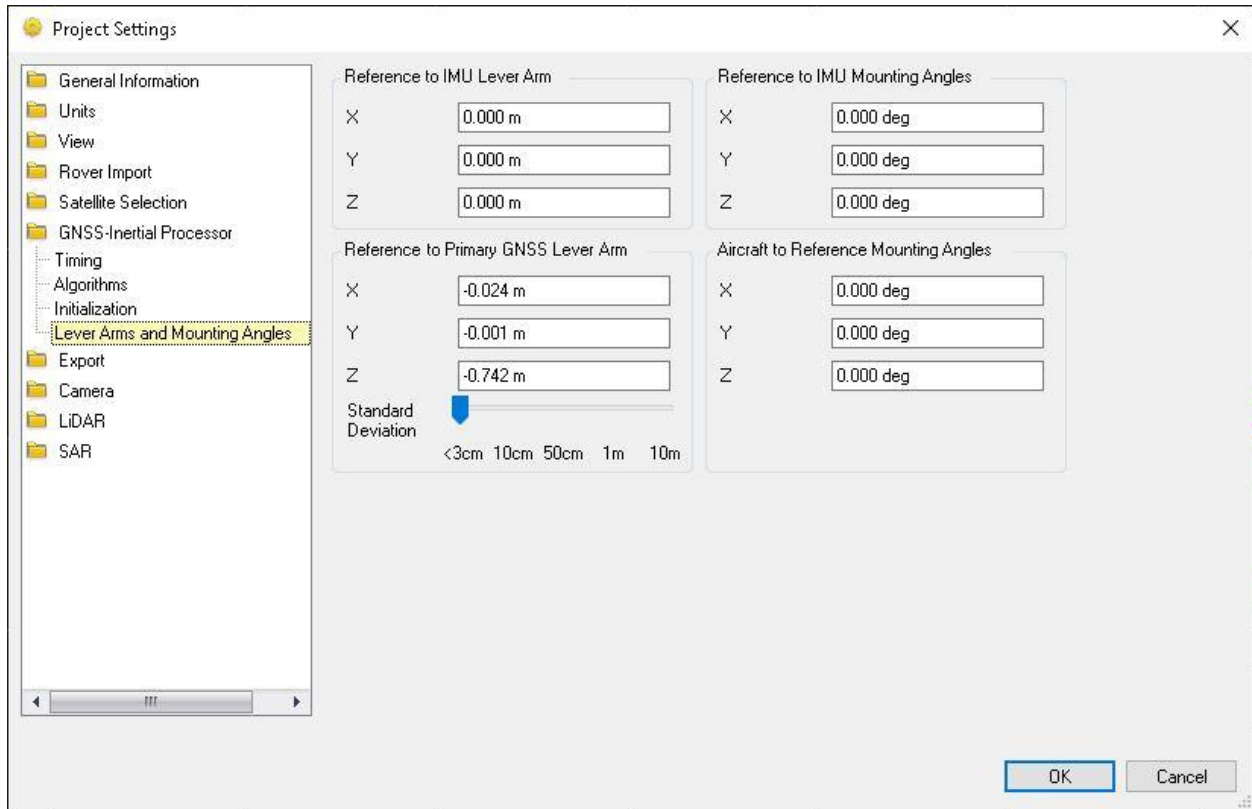


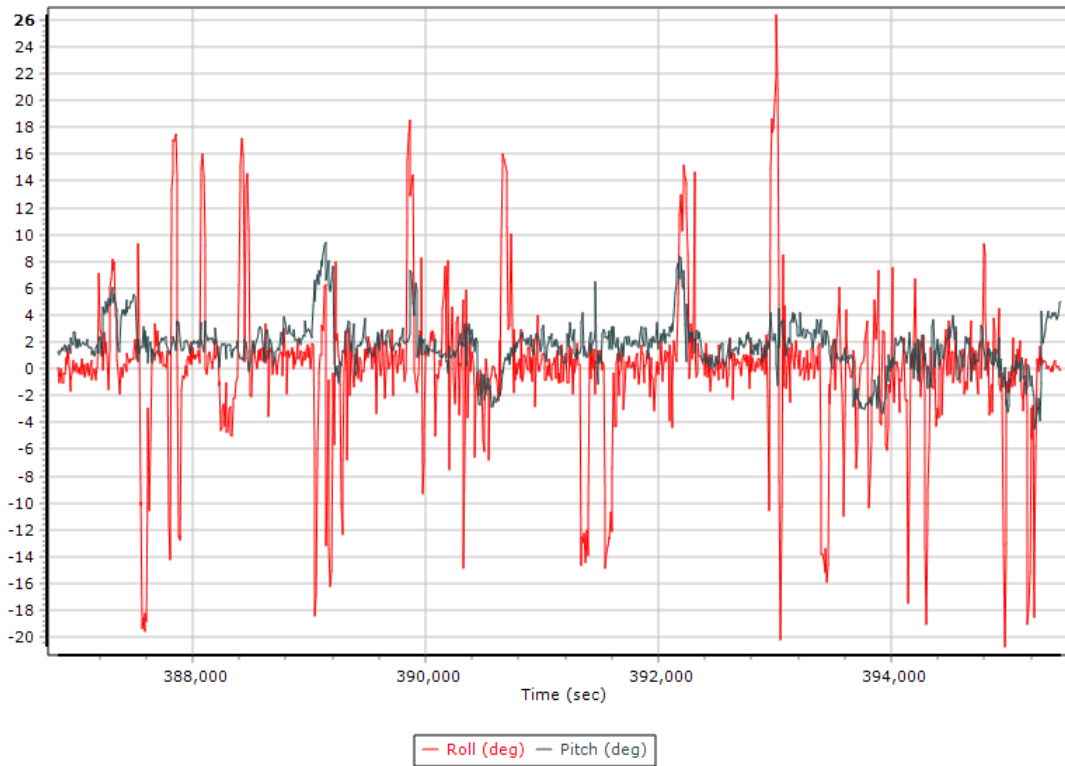
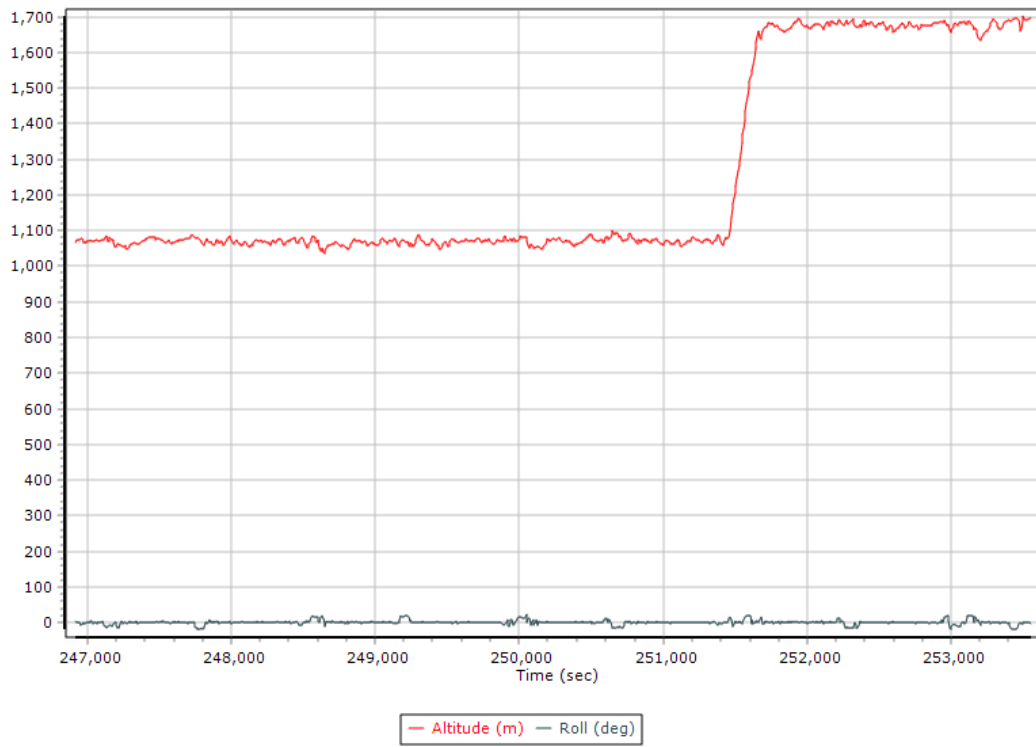


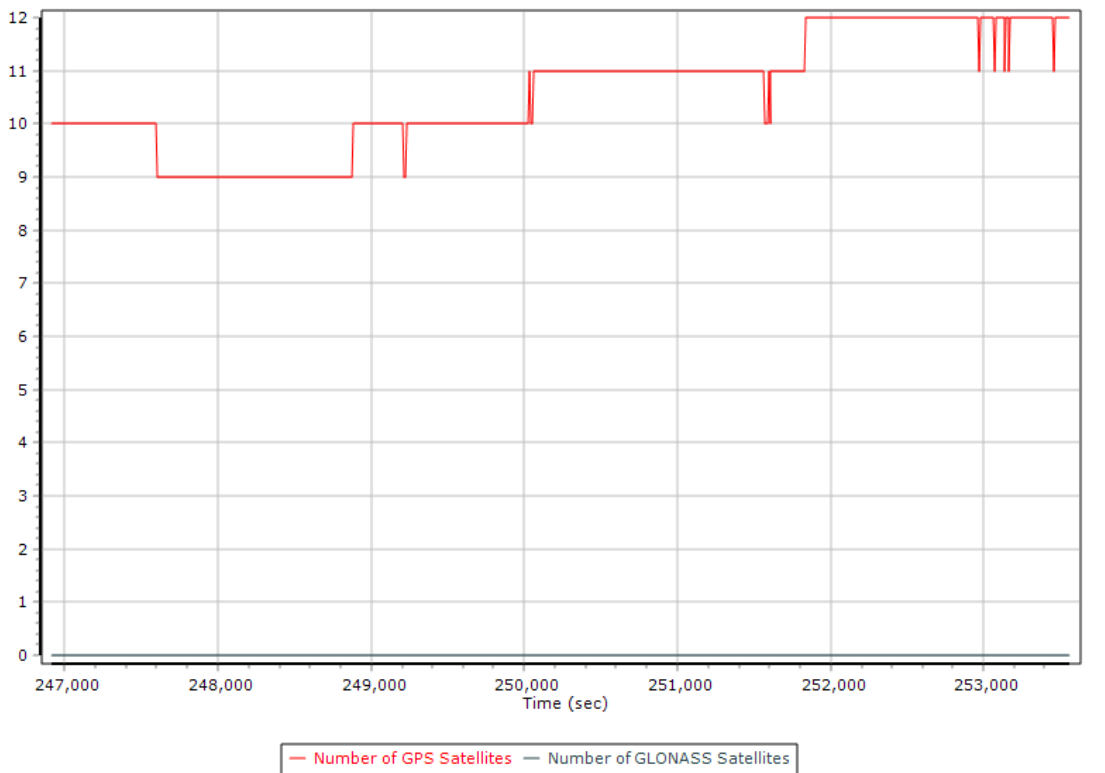
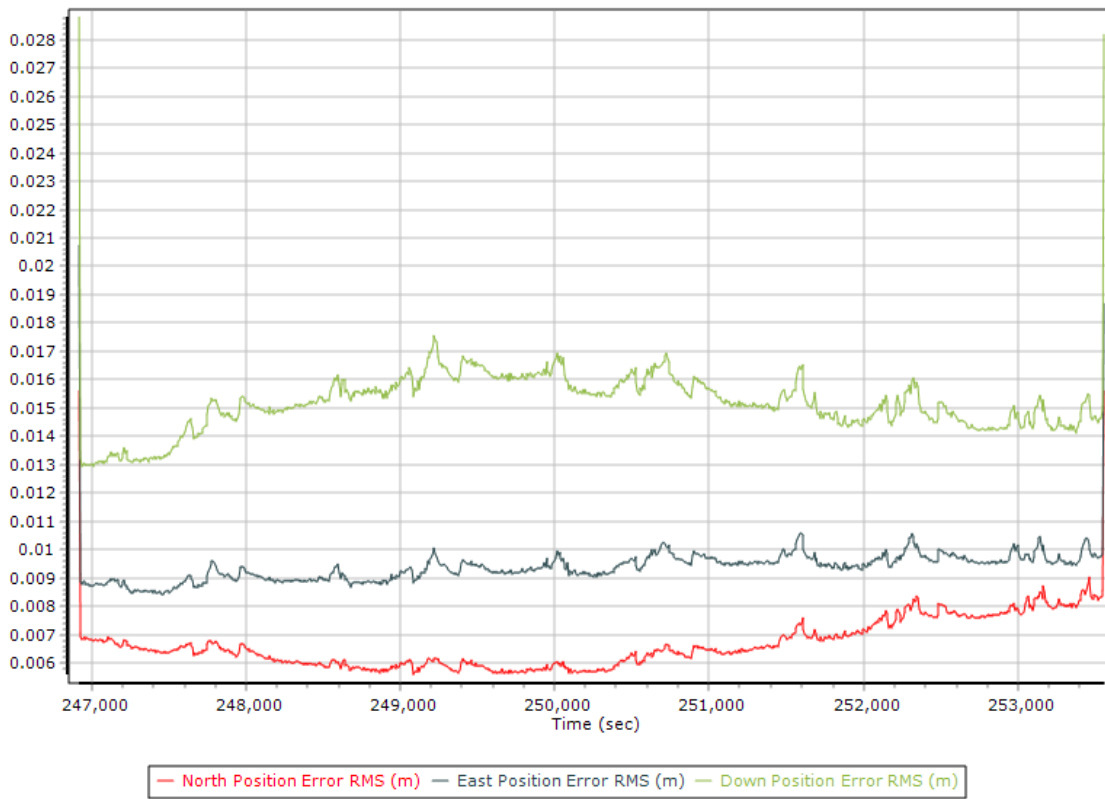


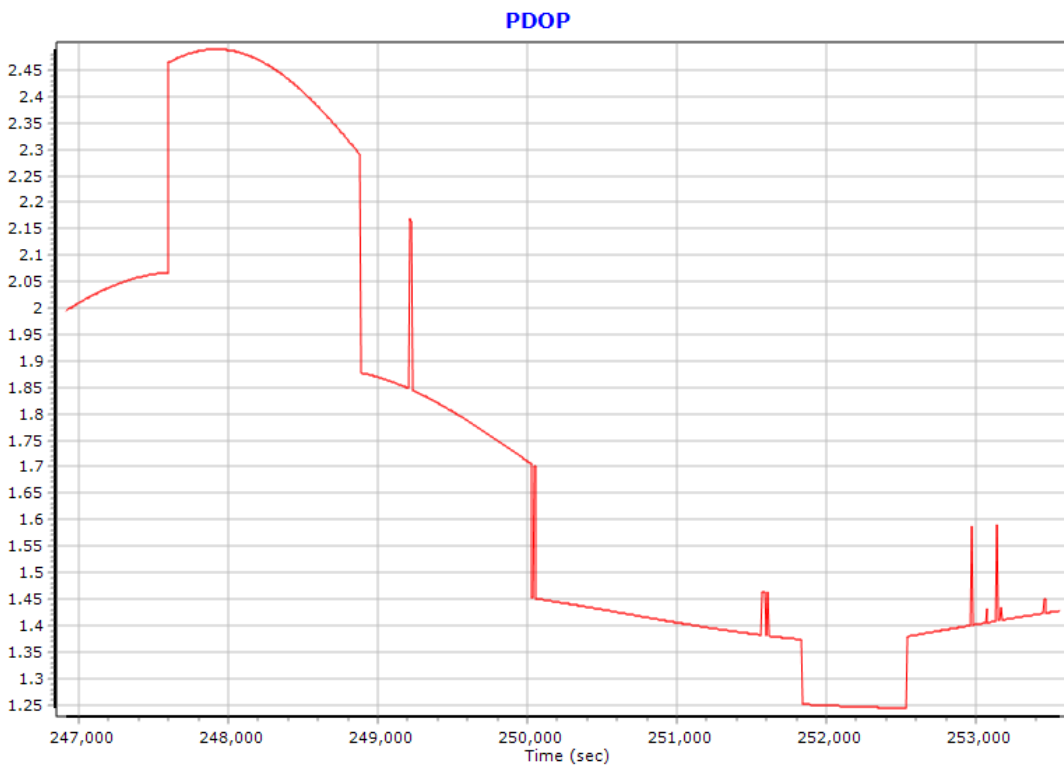
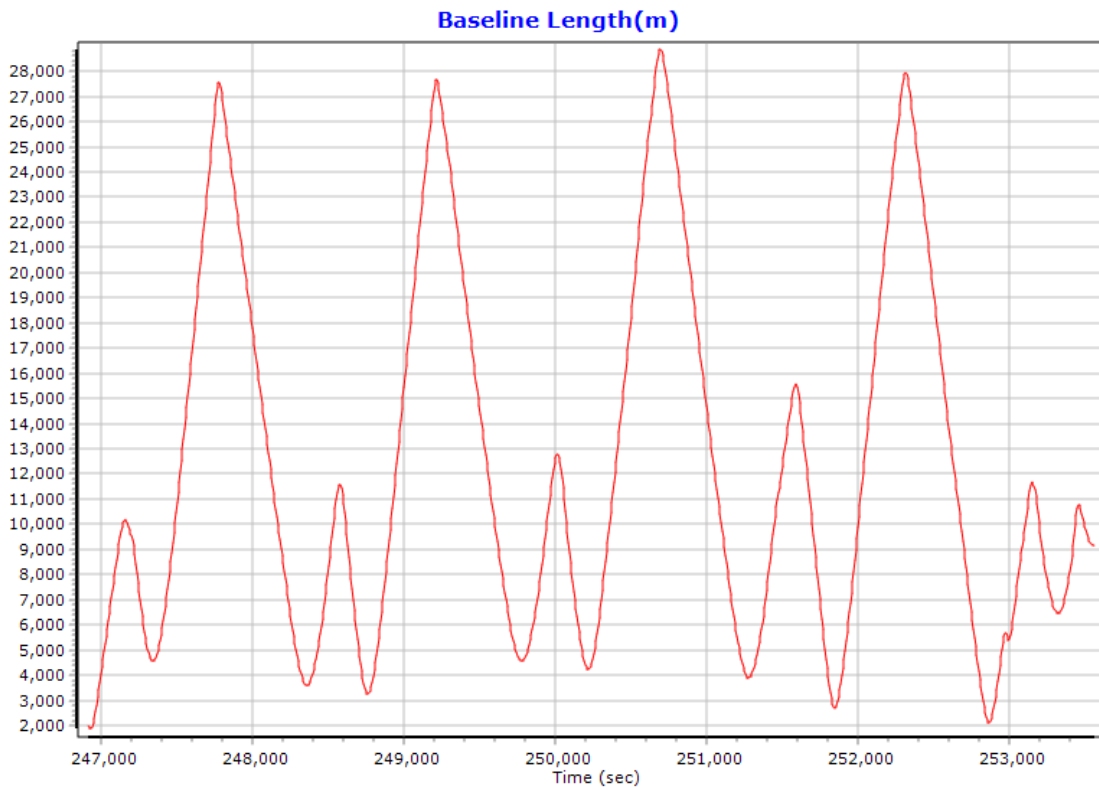
RBV19064A



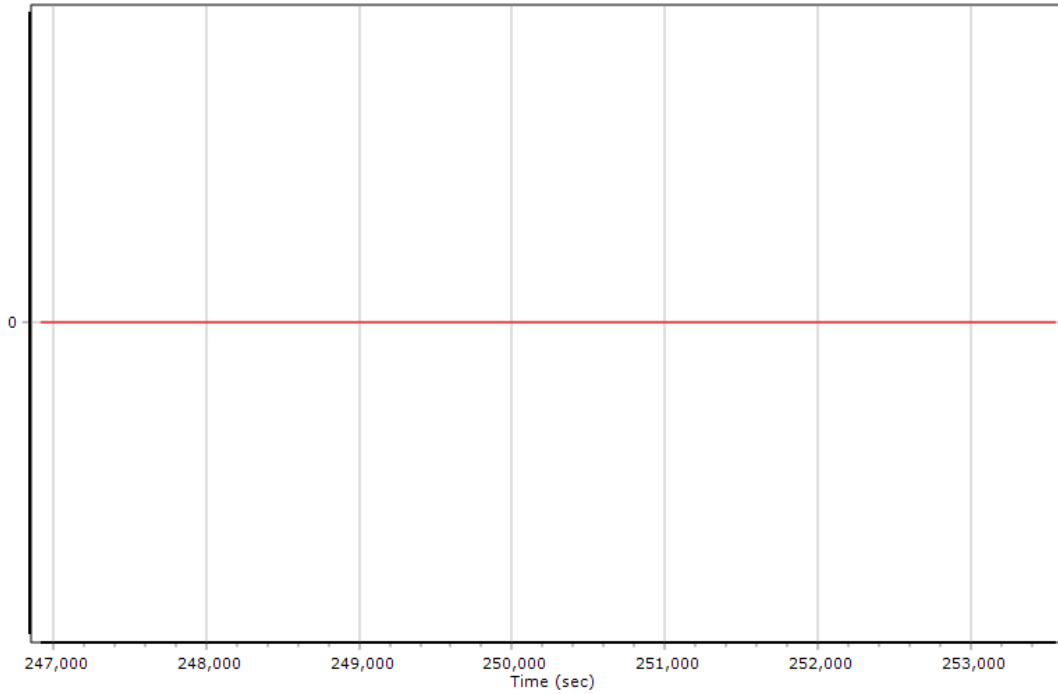






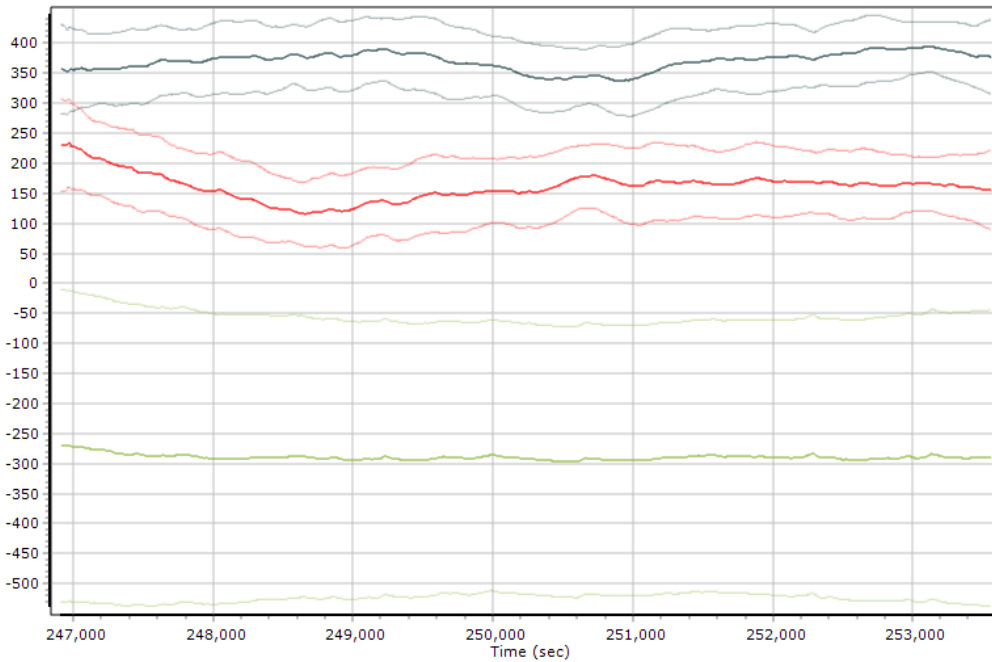


Processing Mode

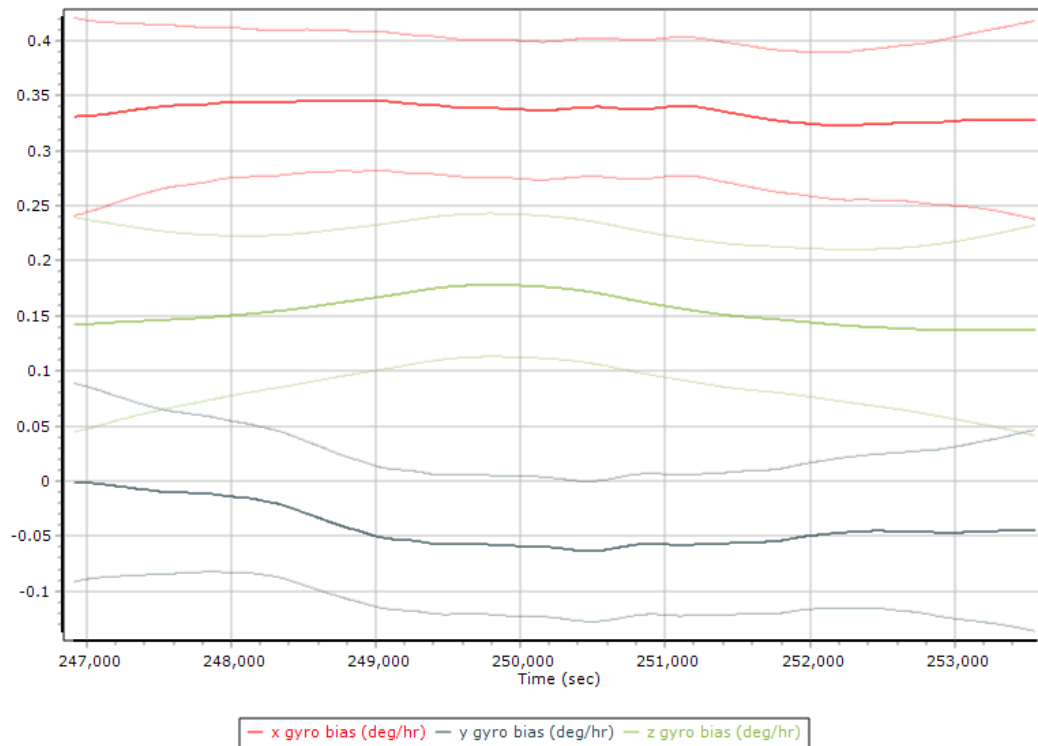
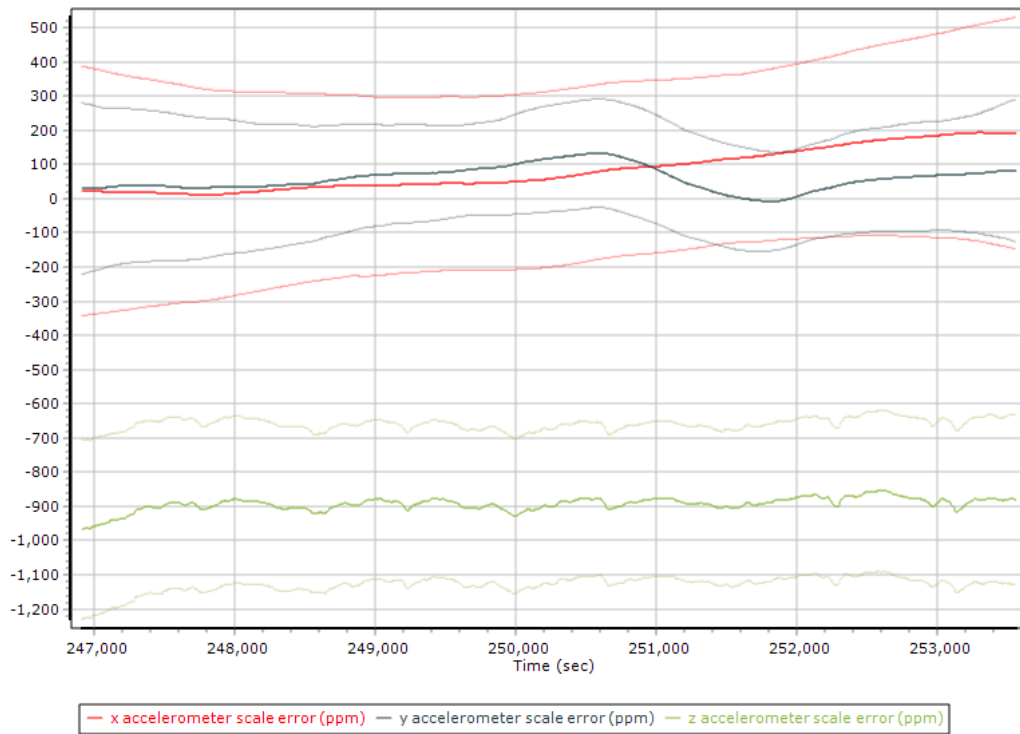


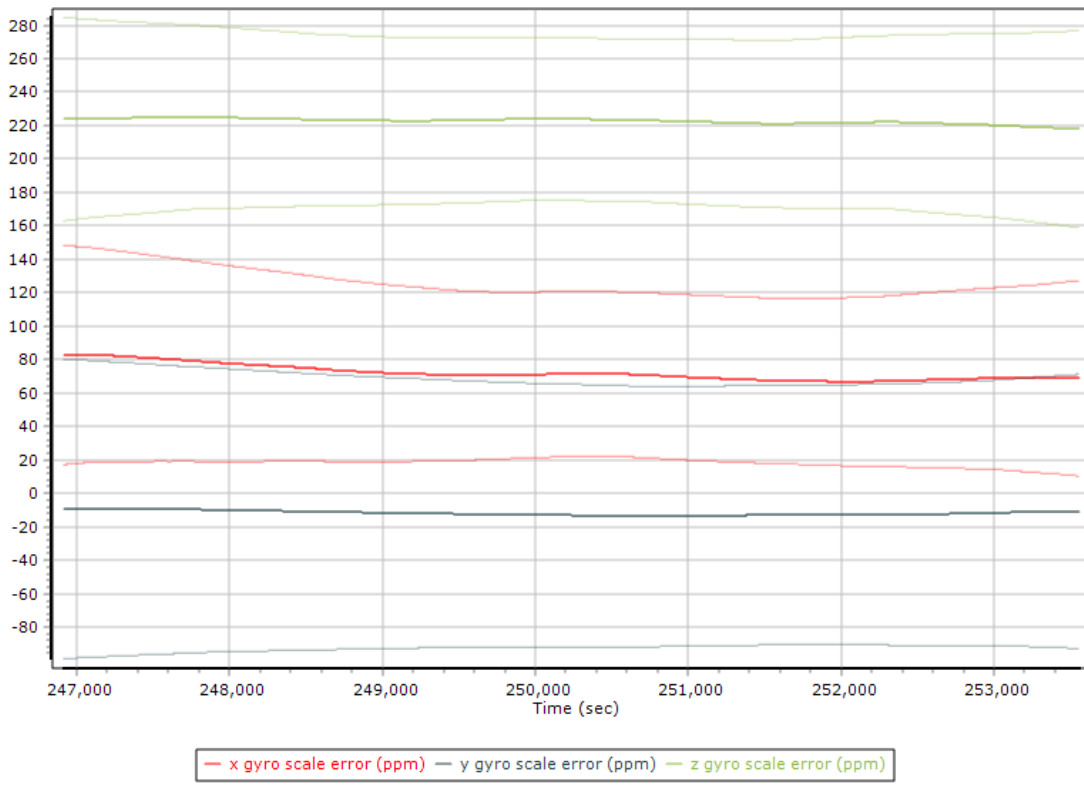
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

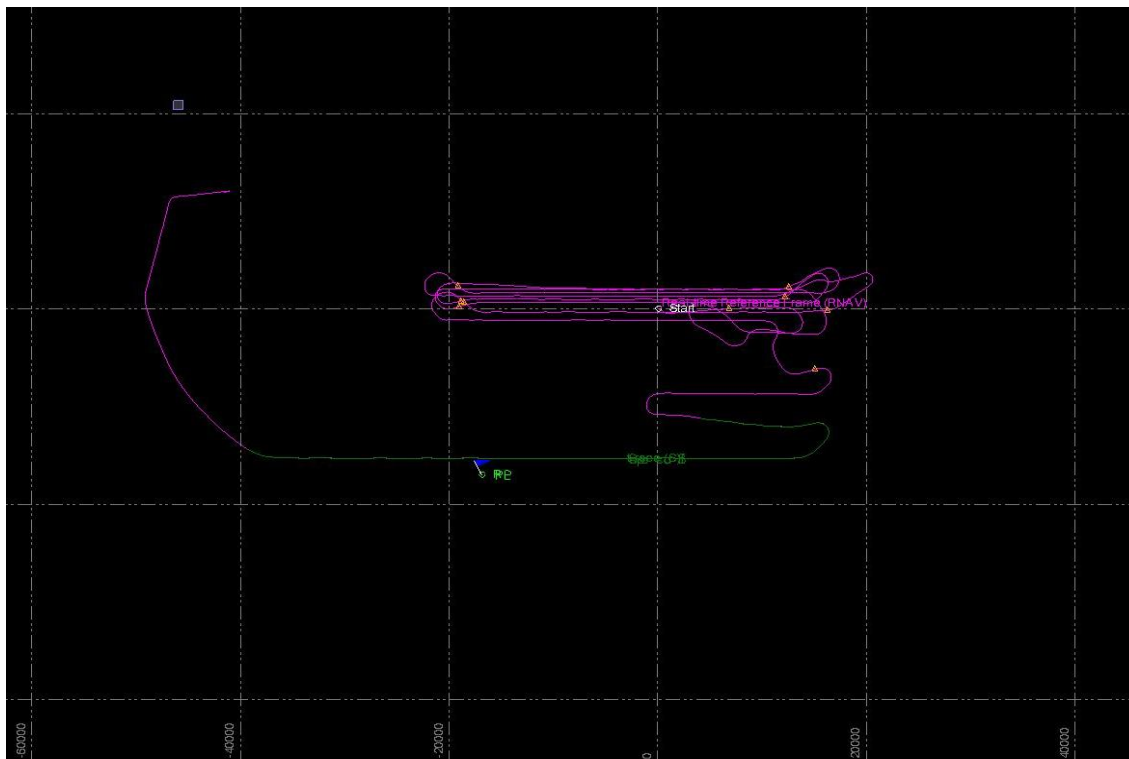


x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)





RBV19064A2



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

X: 0.000 m

Y: 0.000 m

Z: 0.000 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: -0.024 m

Y: -0.001 m

Z: -0.742 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

Timing

Start: 246253.000

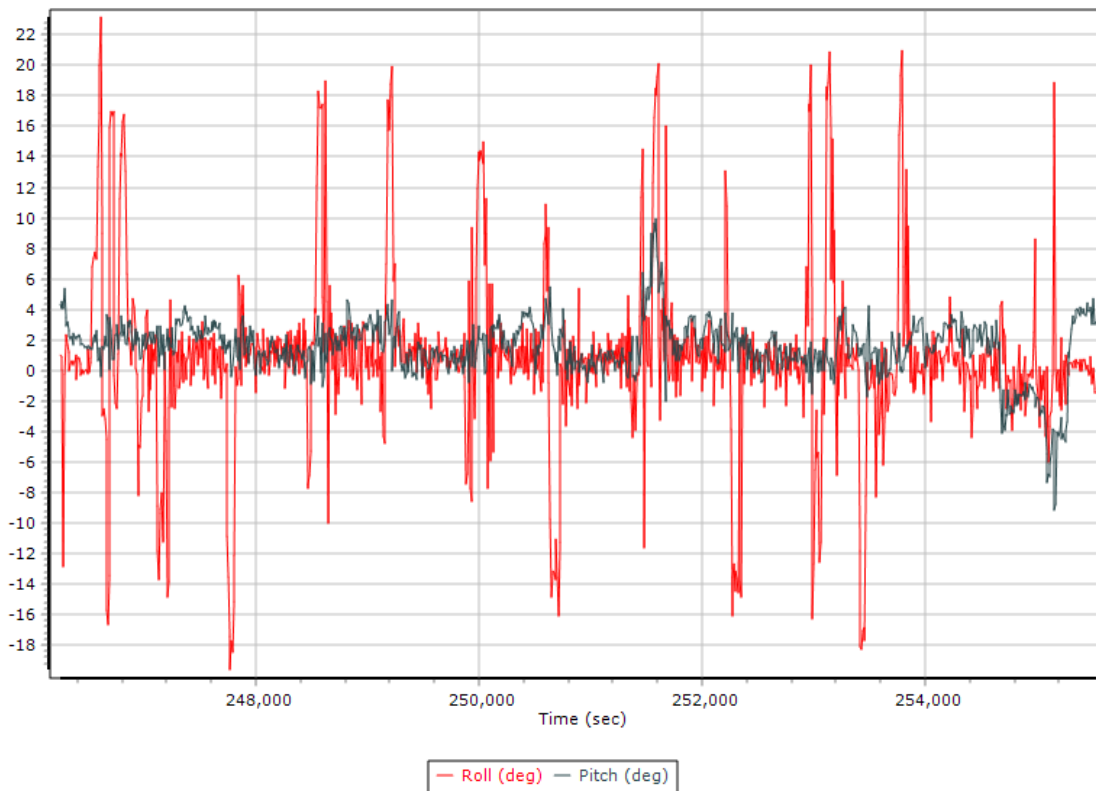
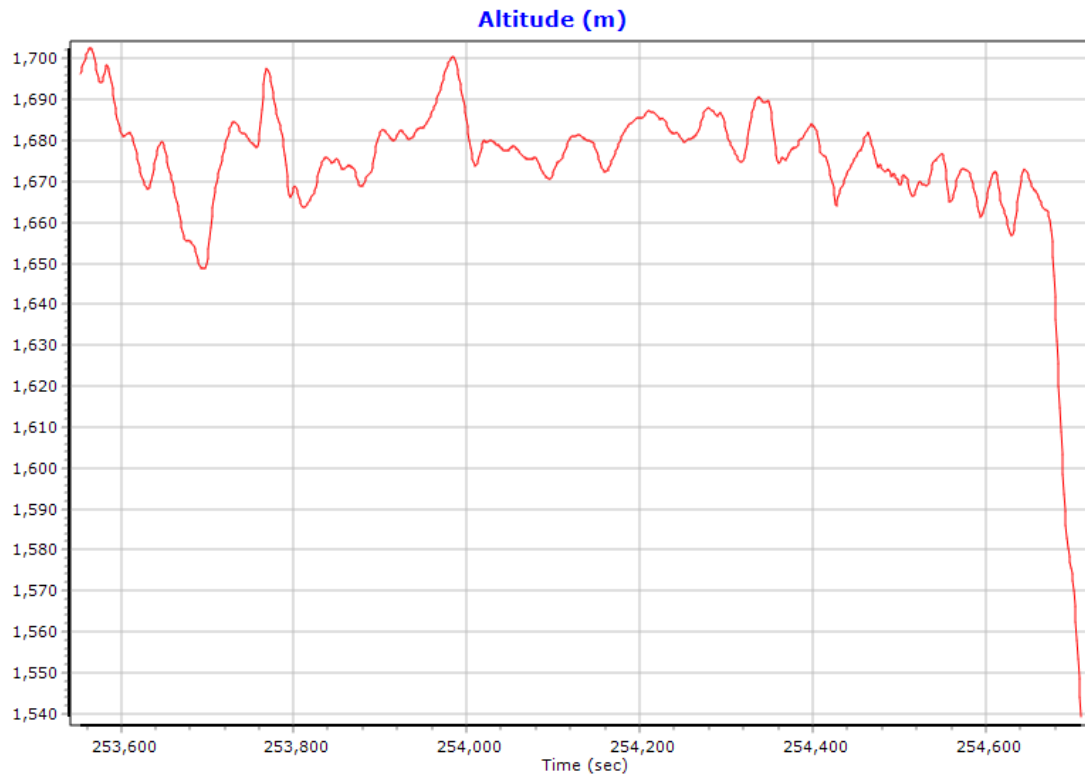
End: 255535.000

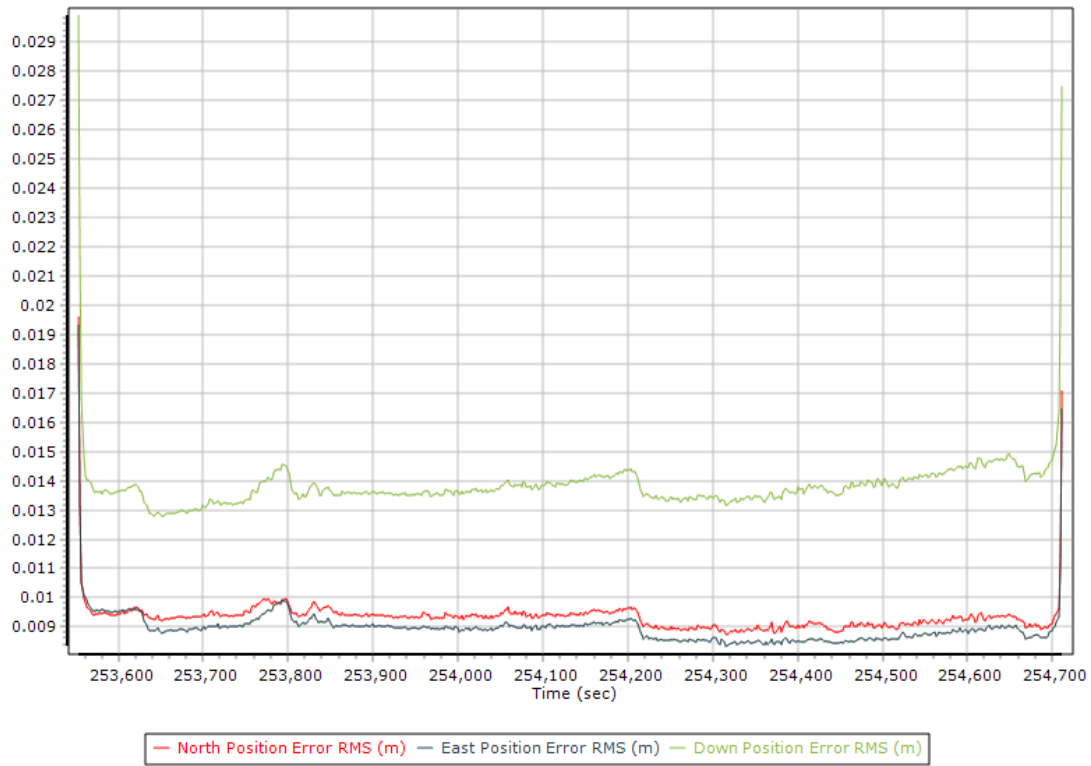
Entire time interval

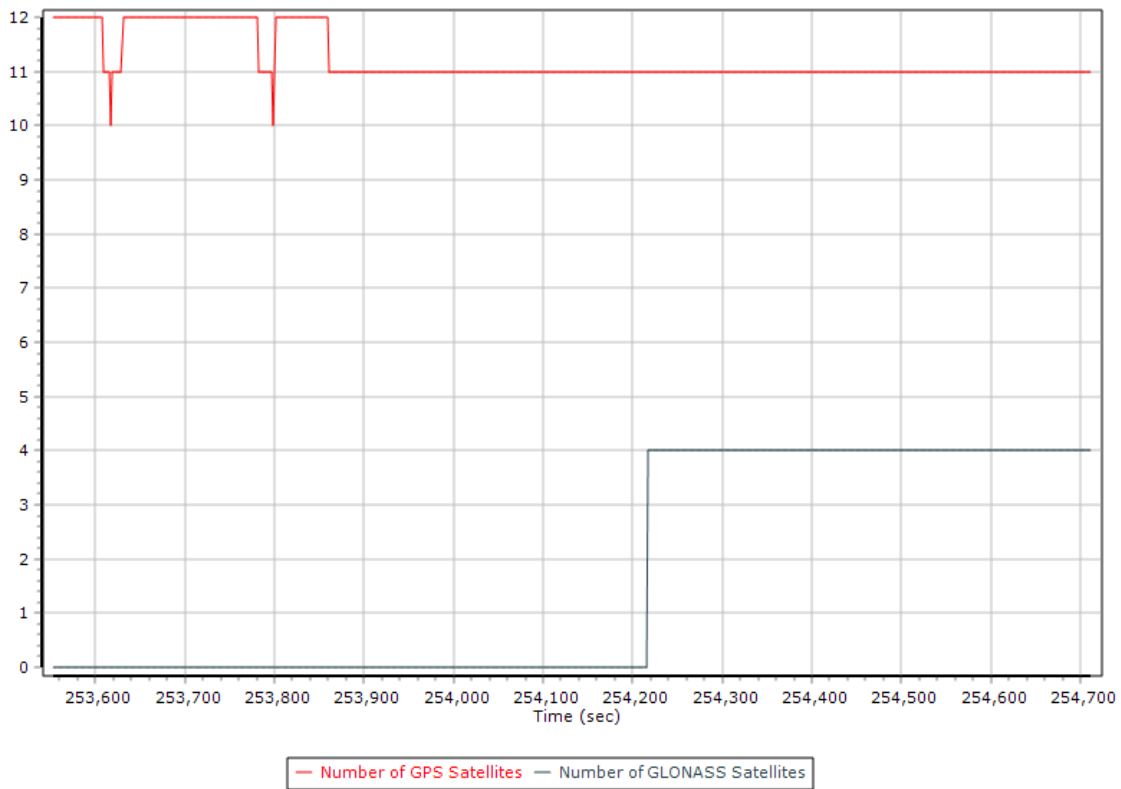
Seconds of start week

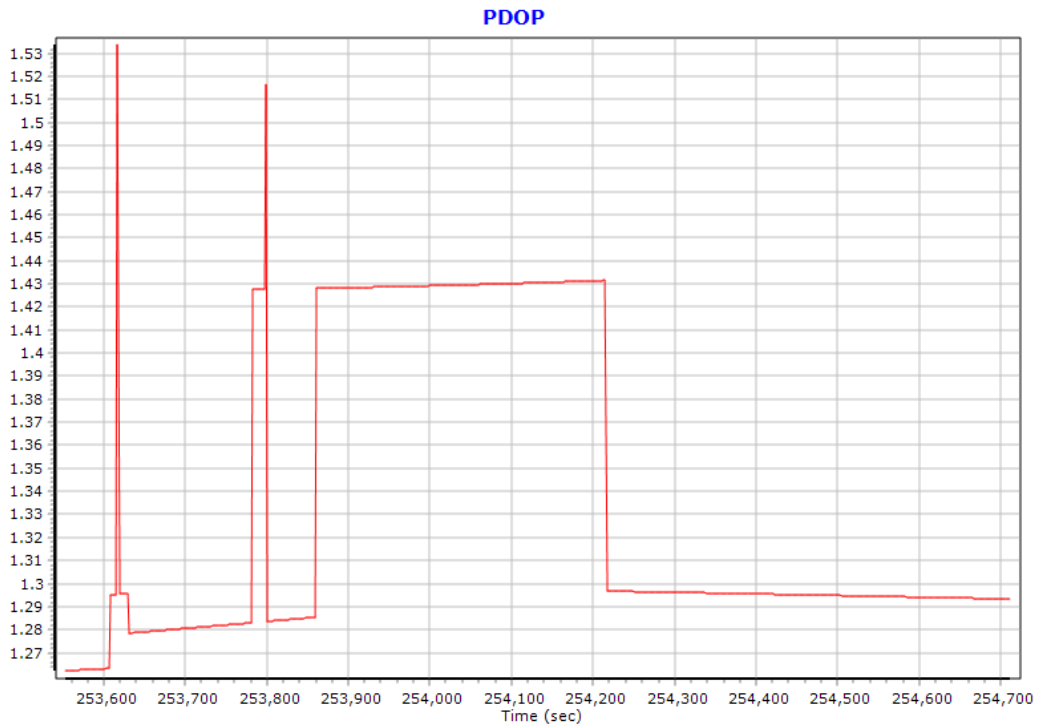
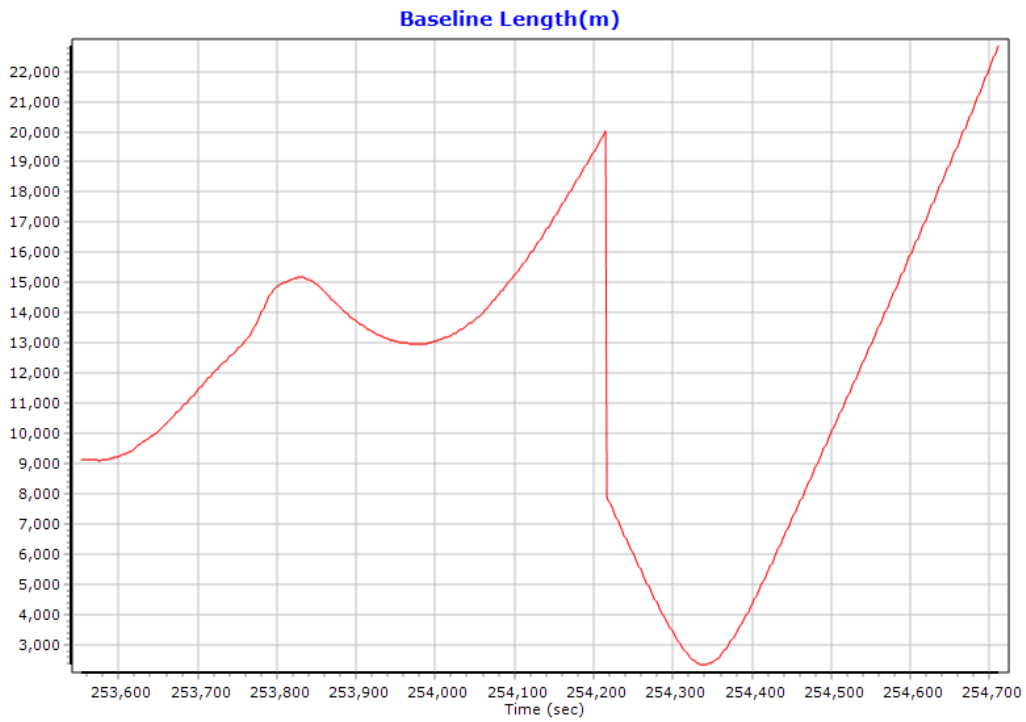
UTC Offset: 18.000

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

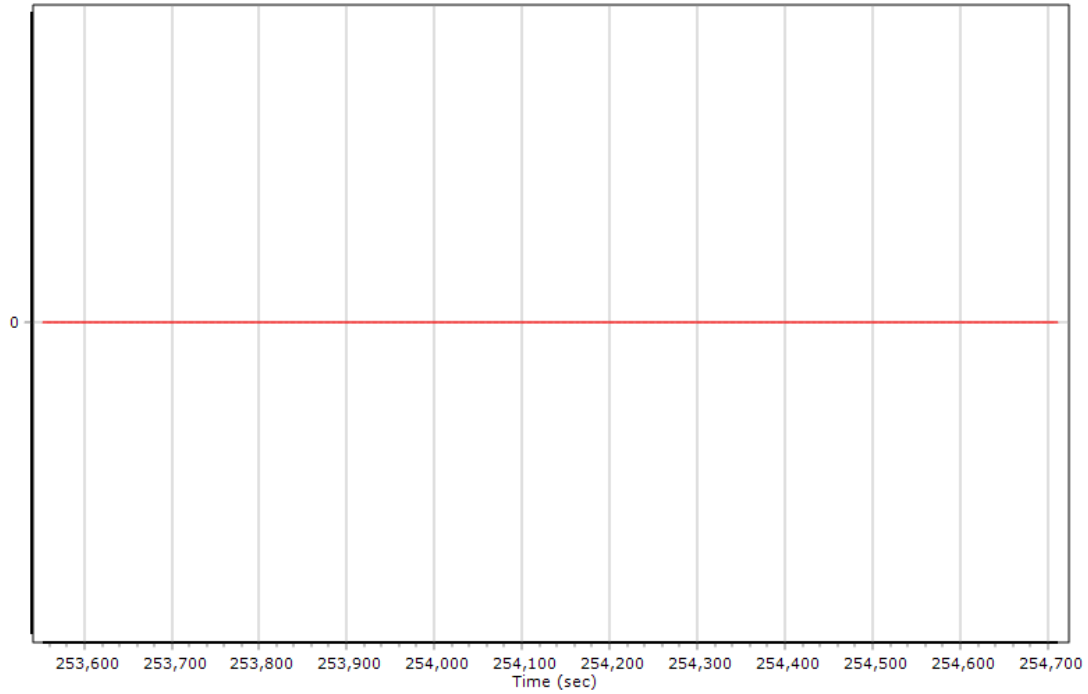






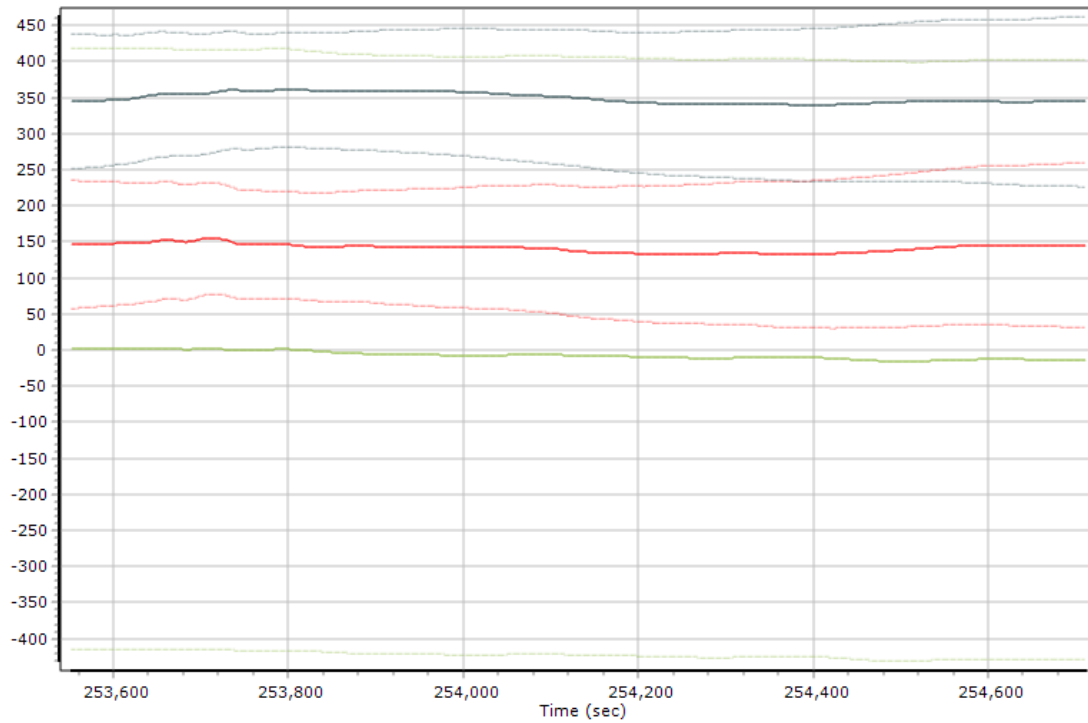


Processing Mode

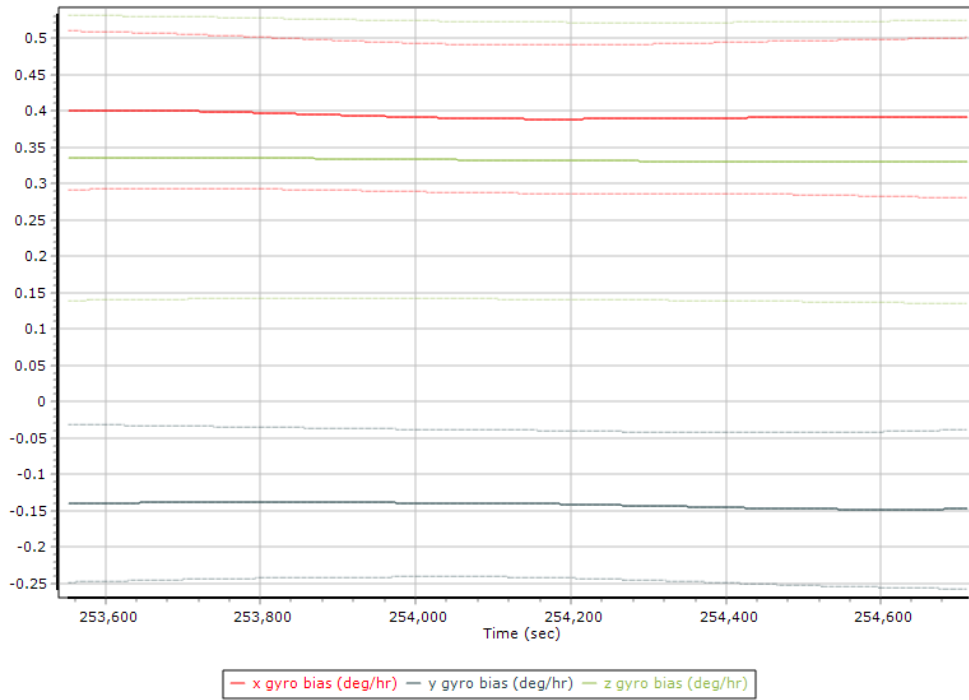
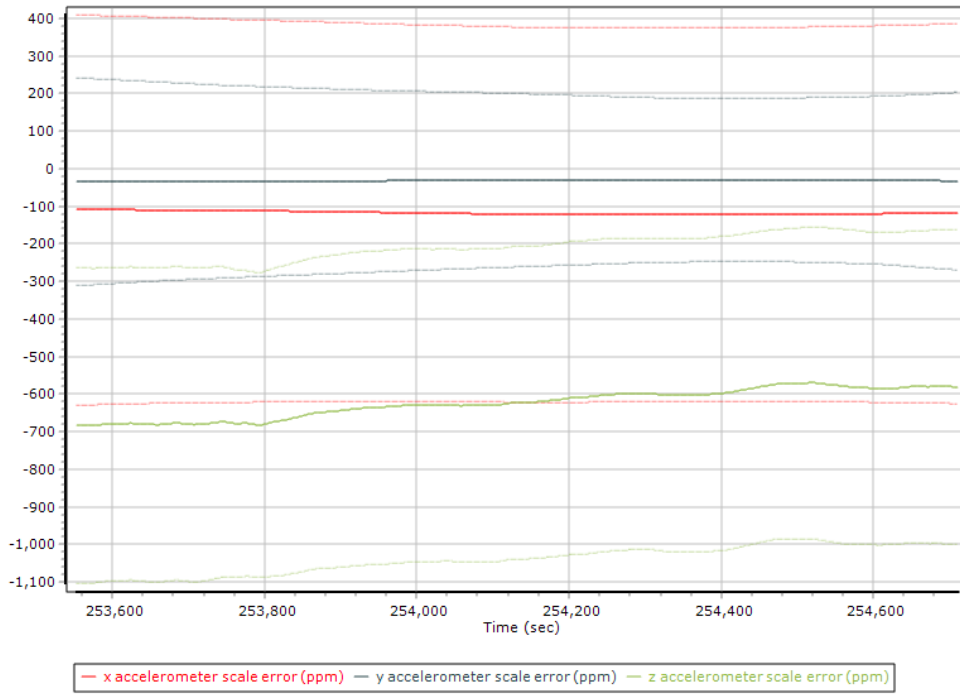


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

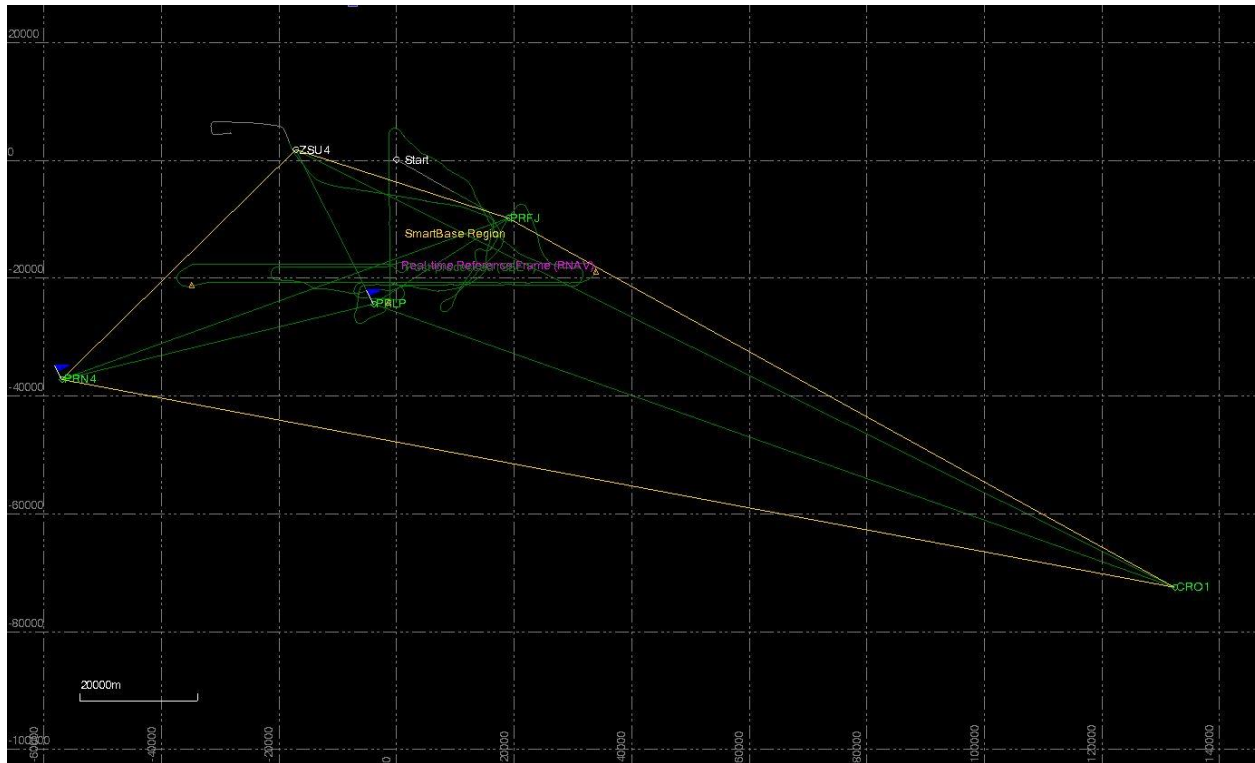


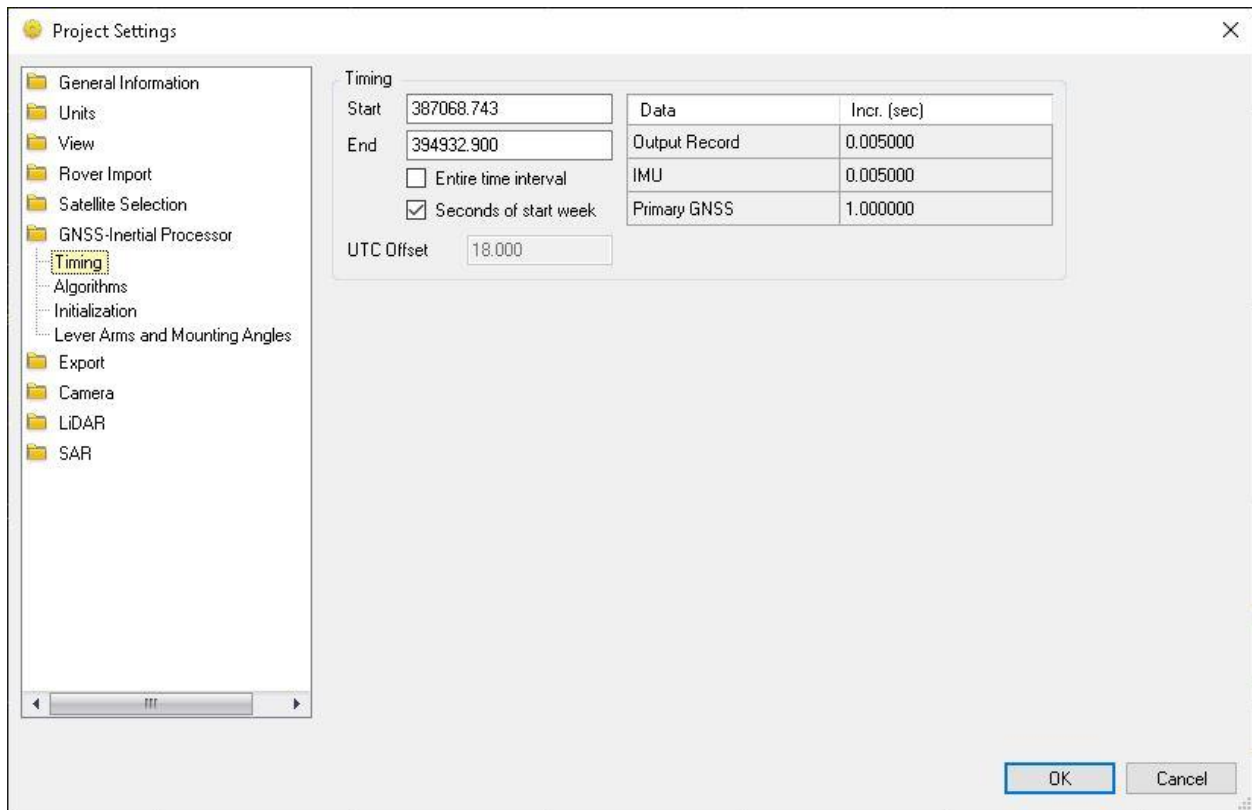
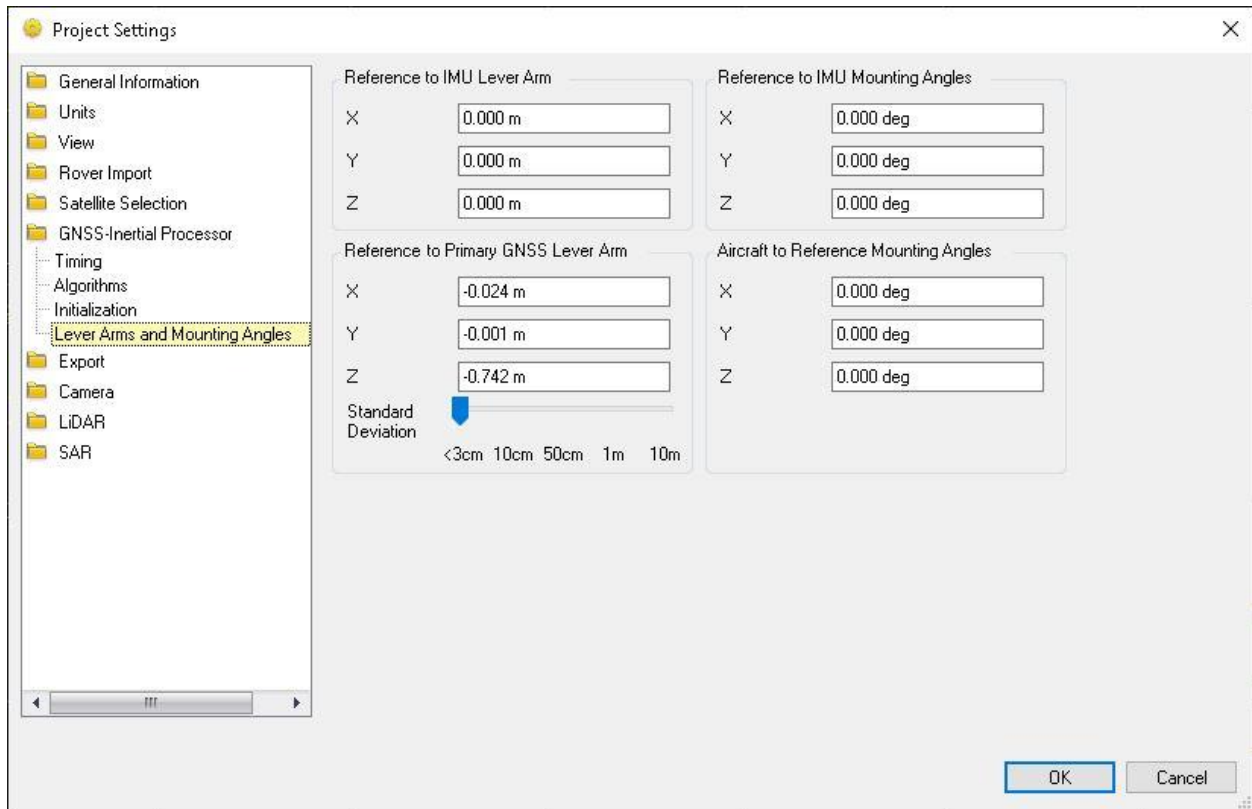
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)

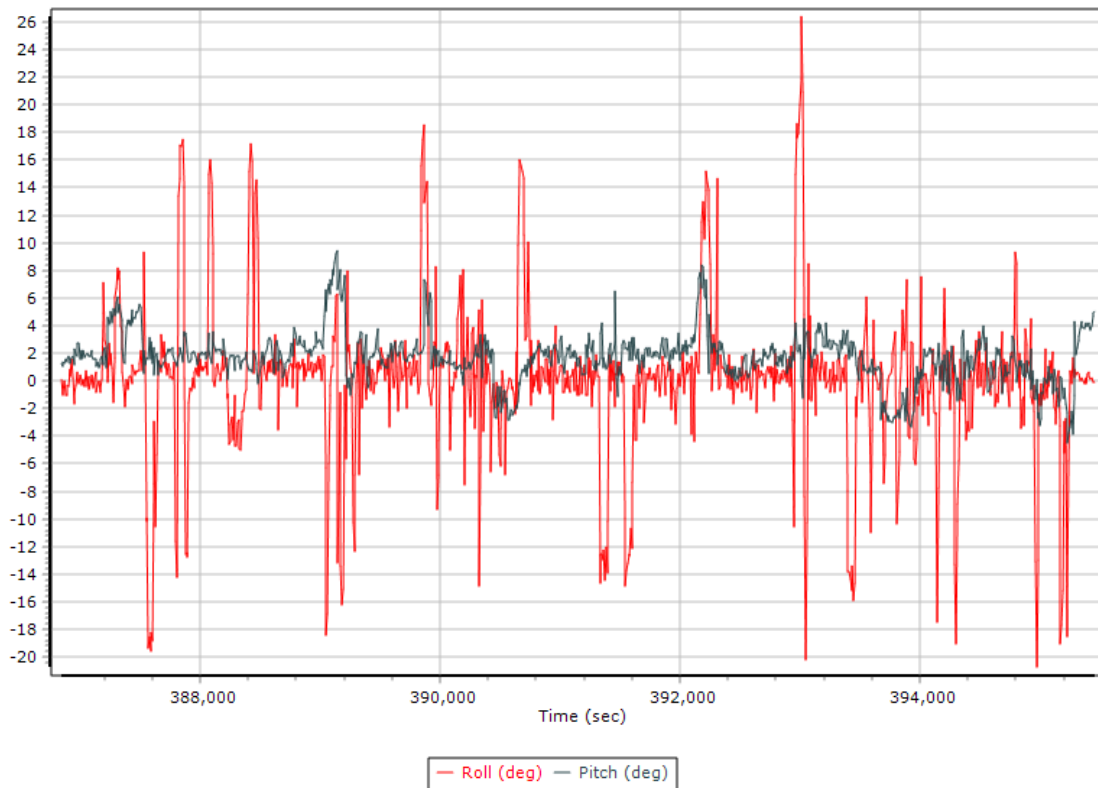
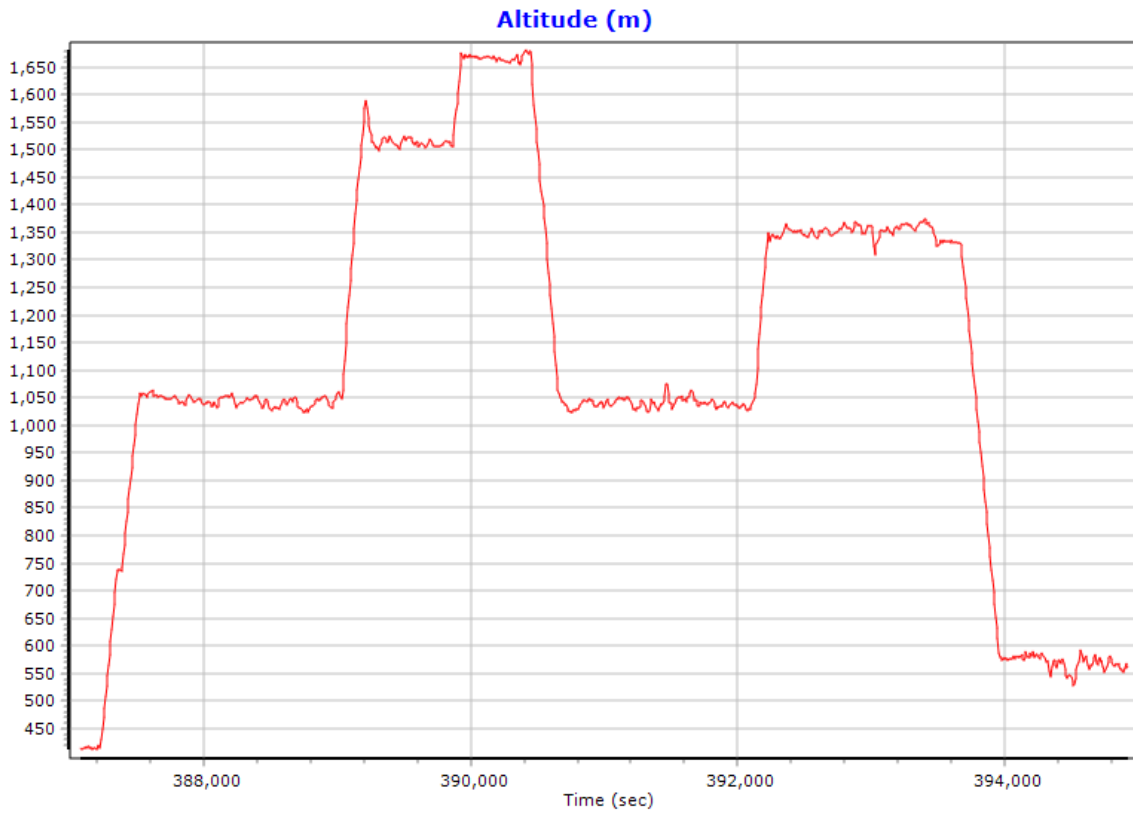


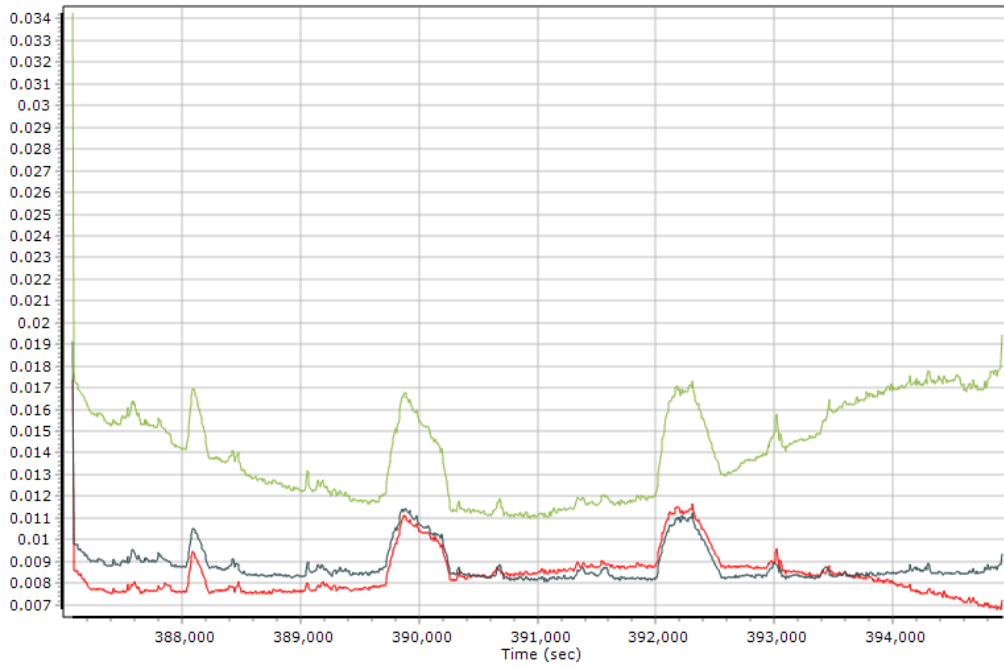


RBV18066A

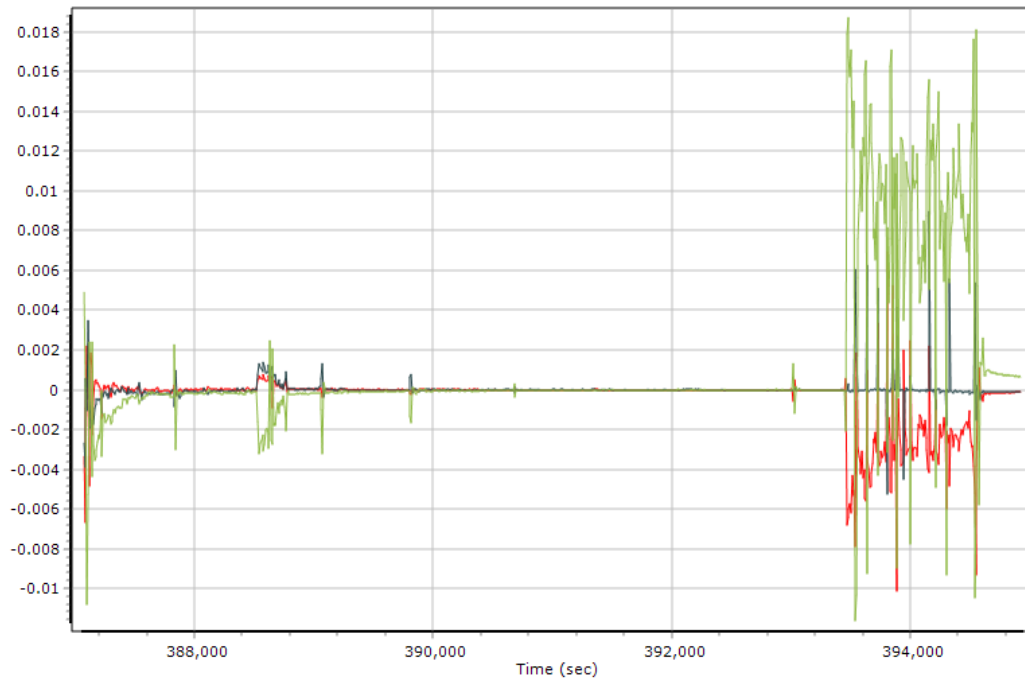




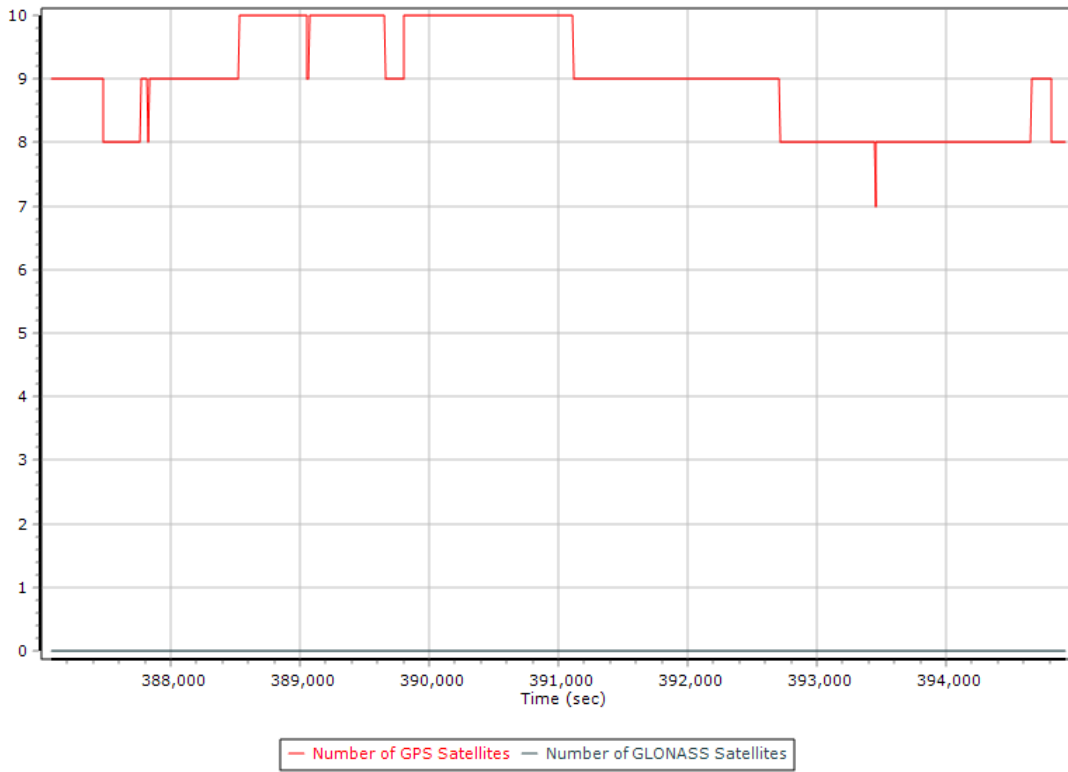




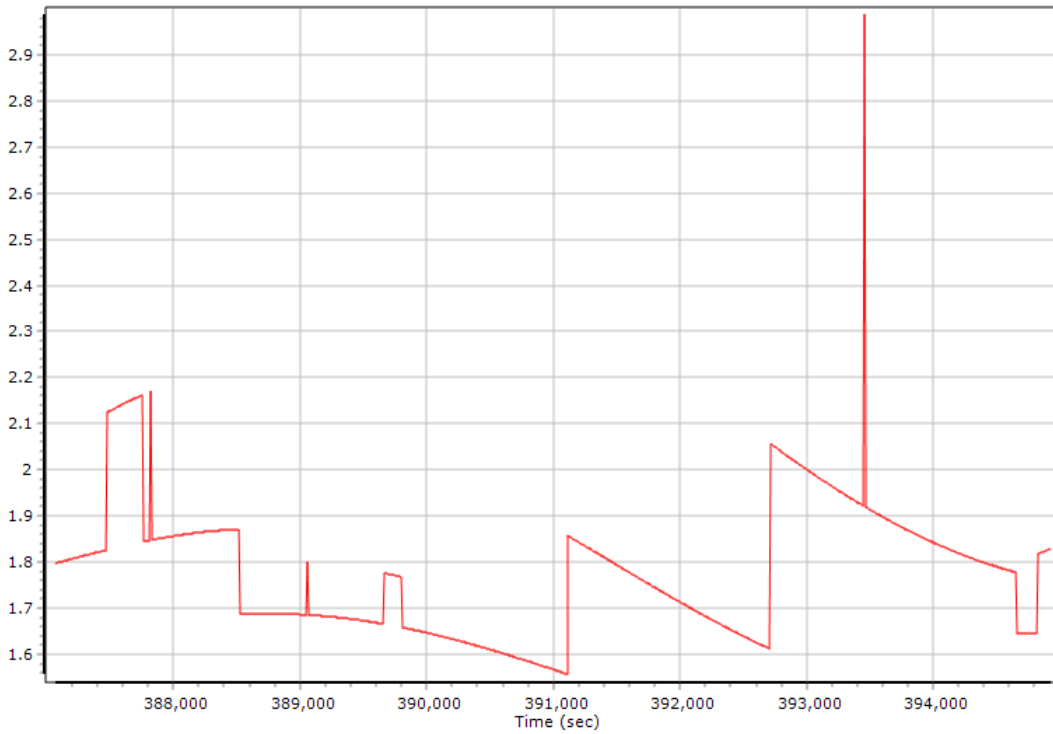
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



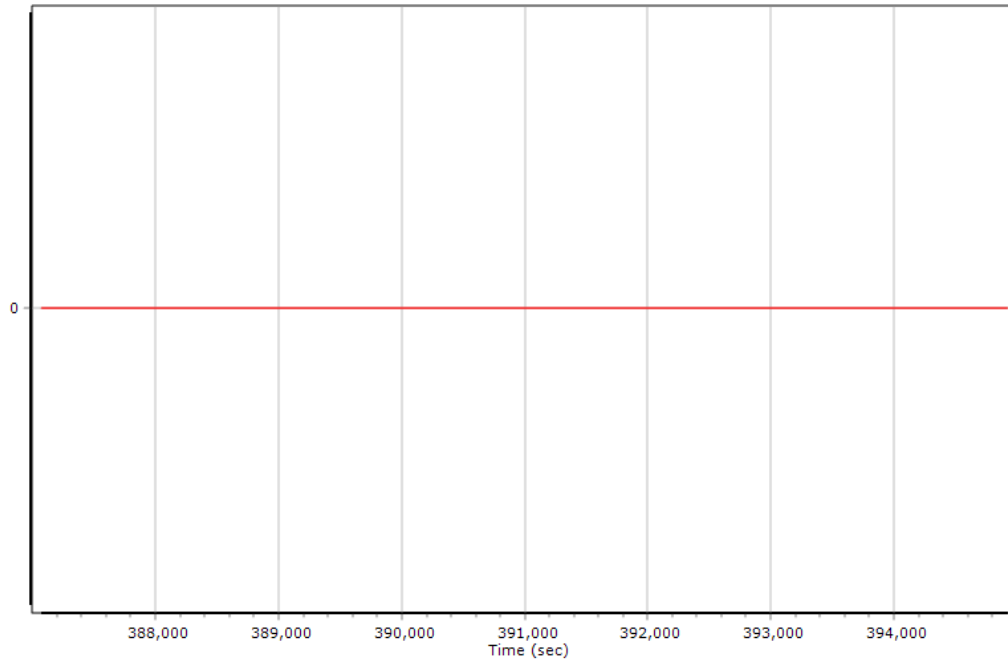
— North (m) — East (m) — Down (m) — DR mode



PDOP

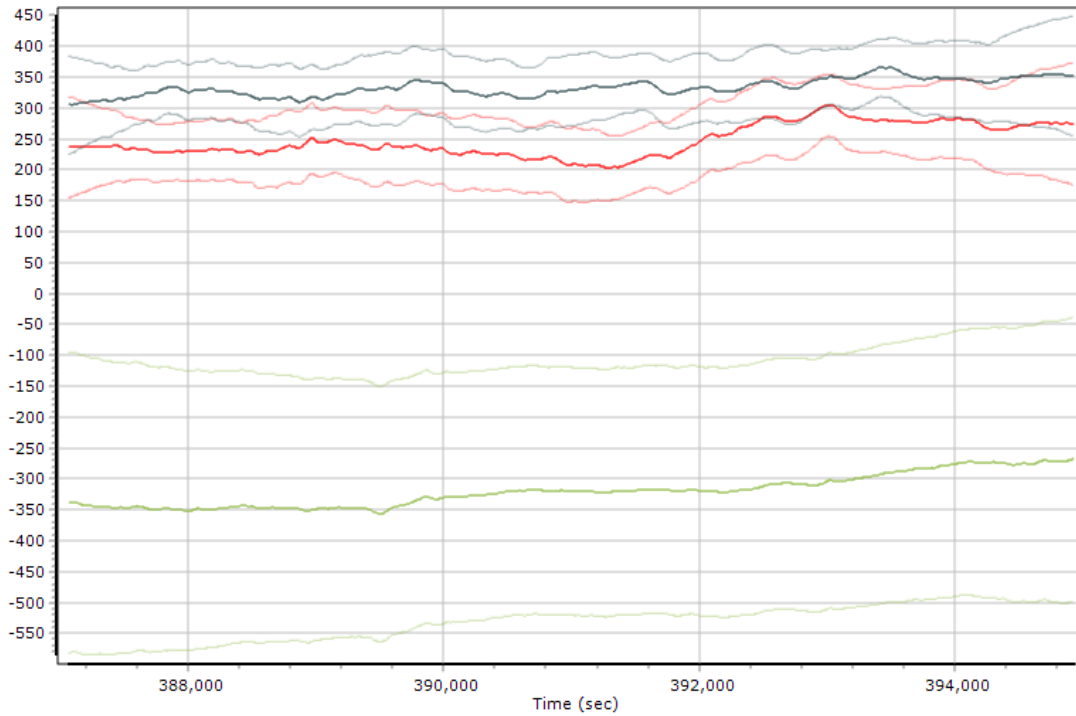


Processing Mode

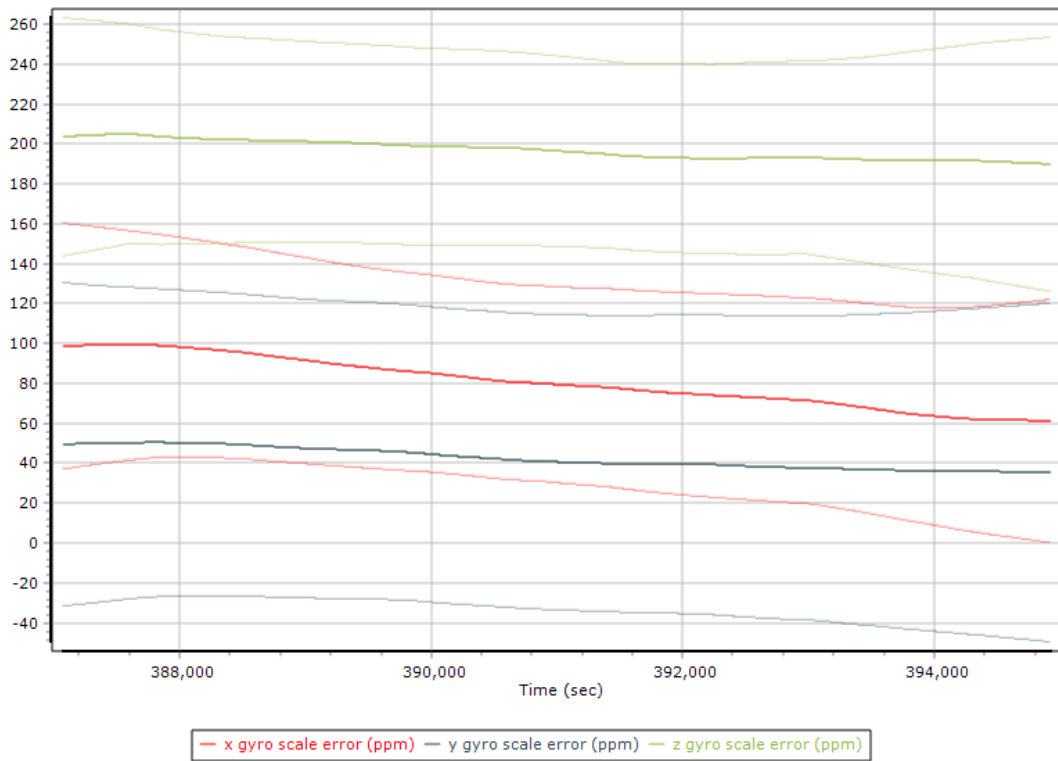
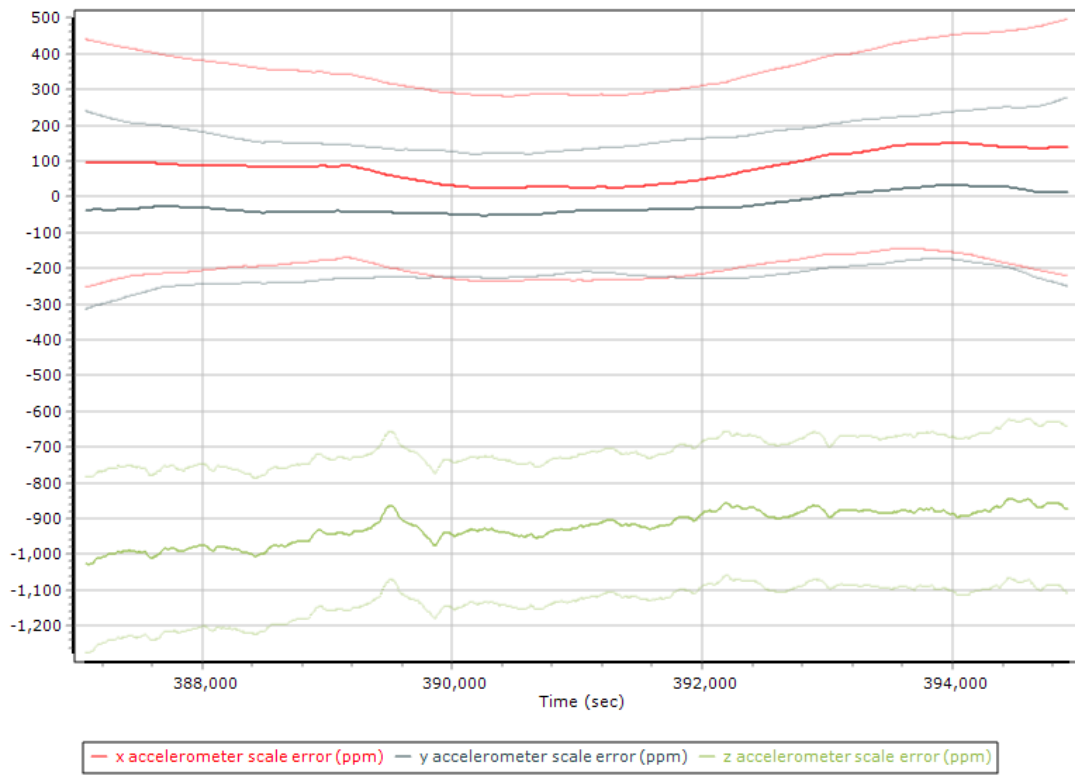


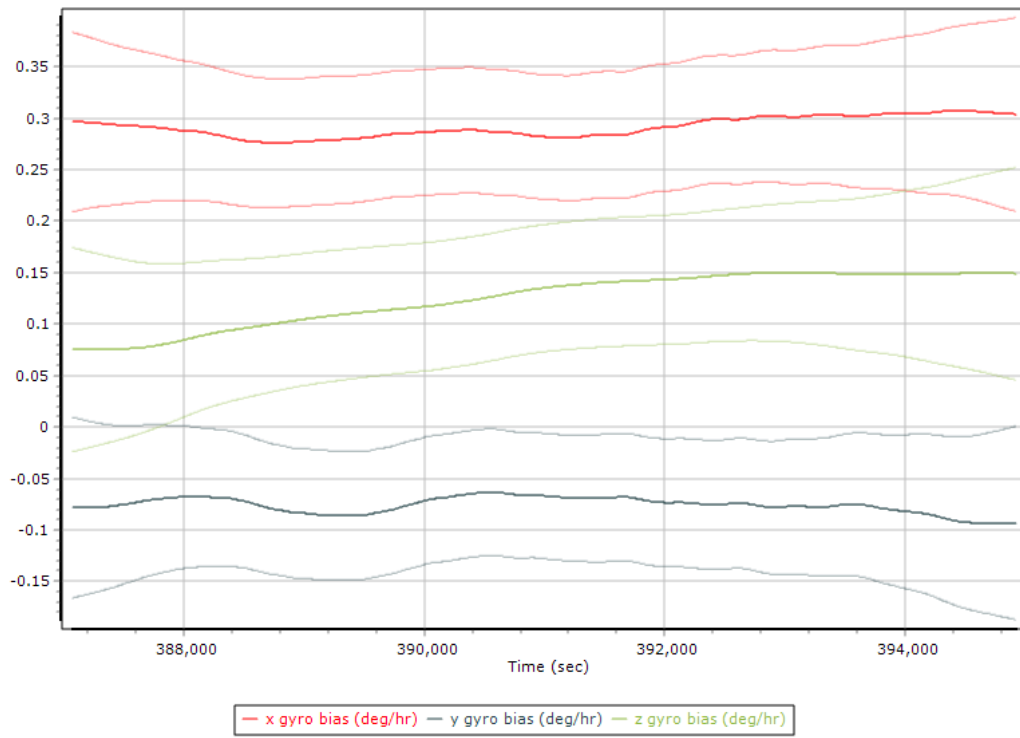
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

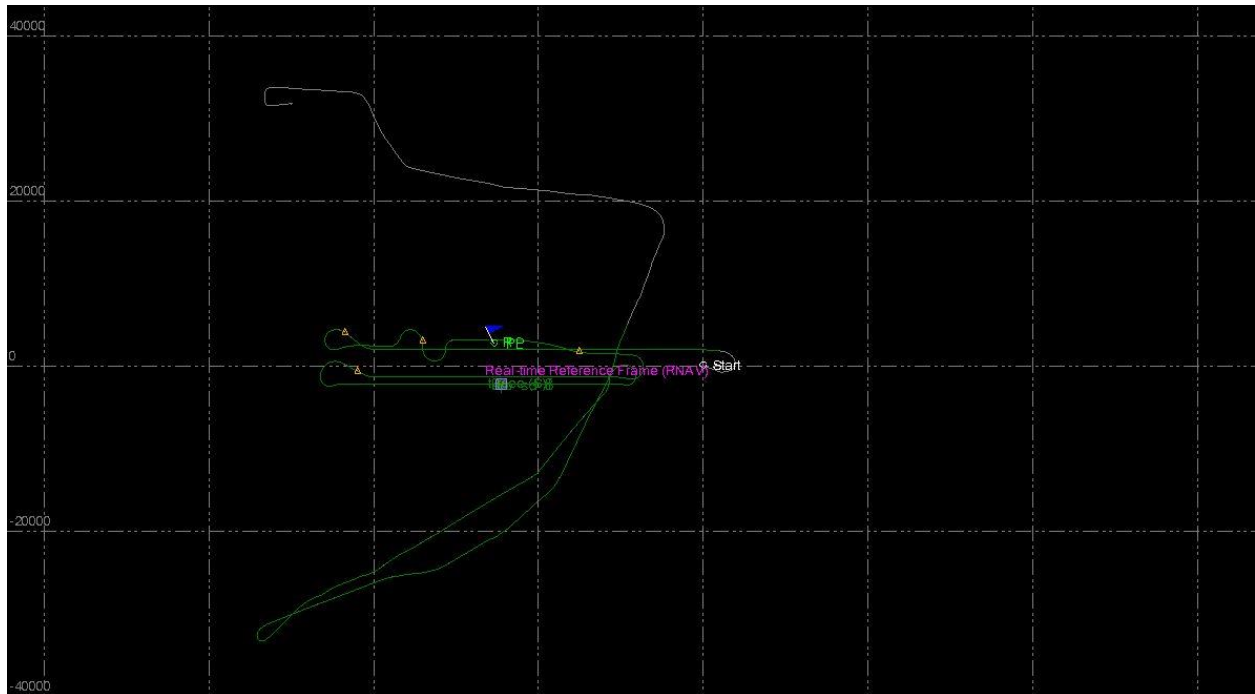


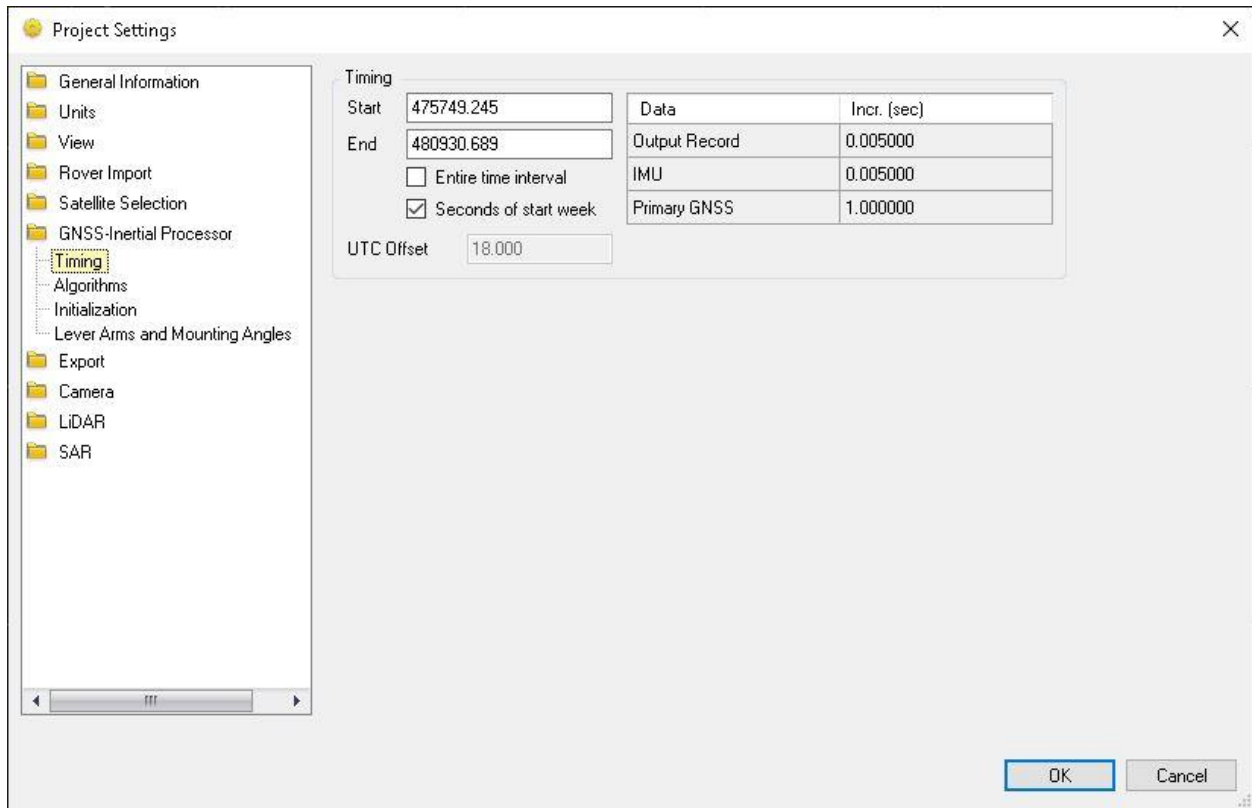
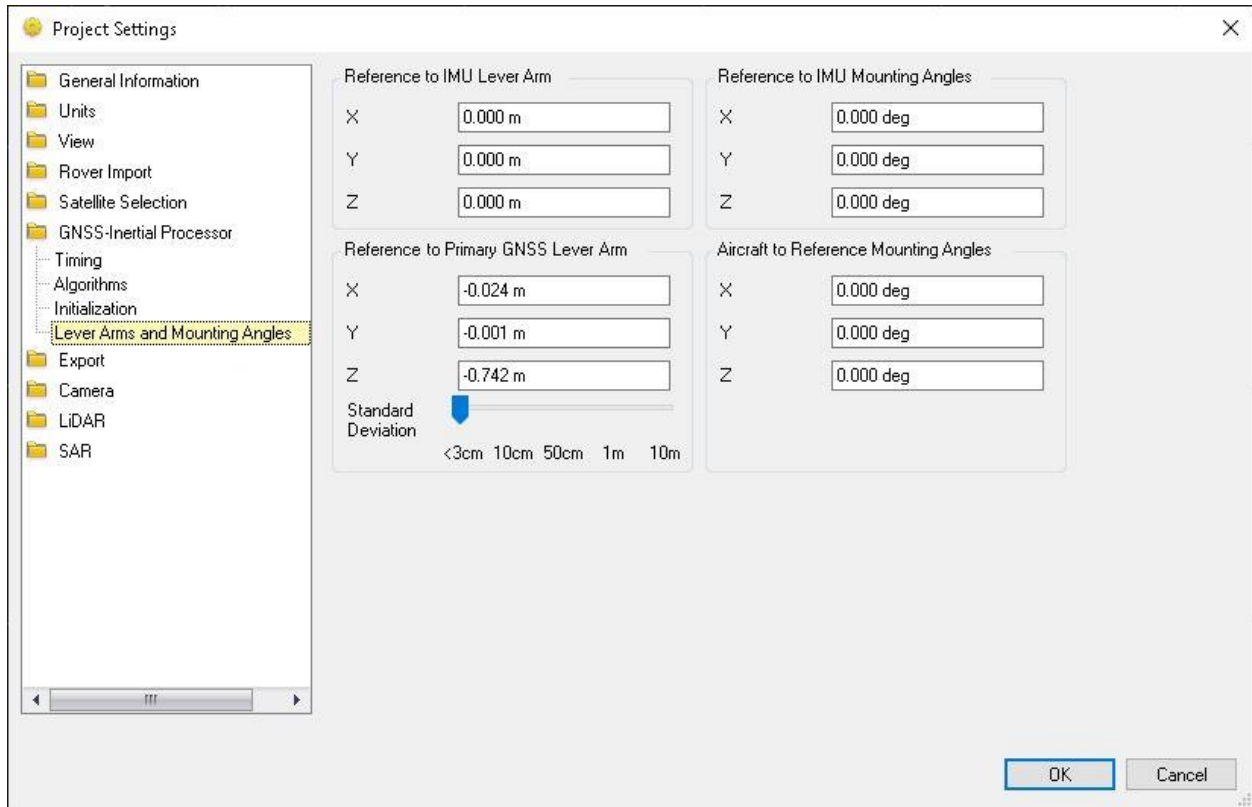
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)

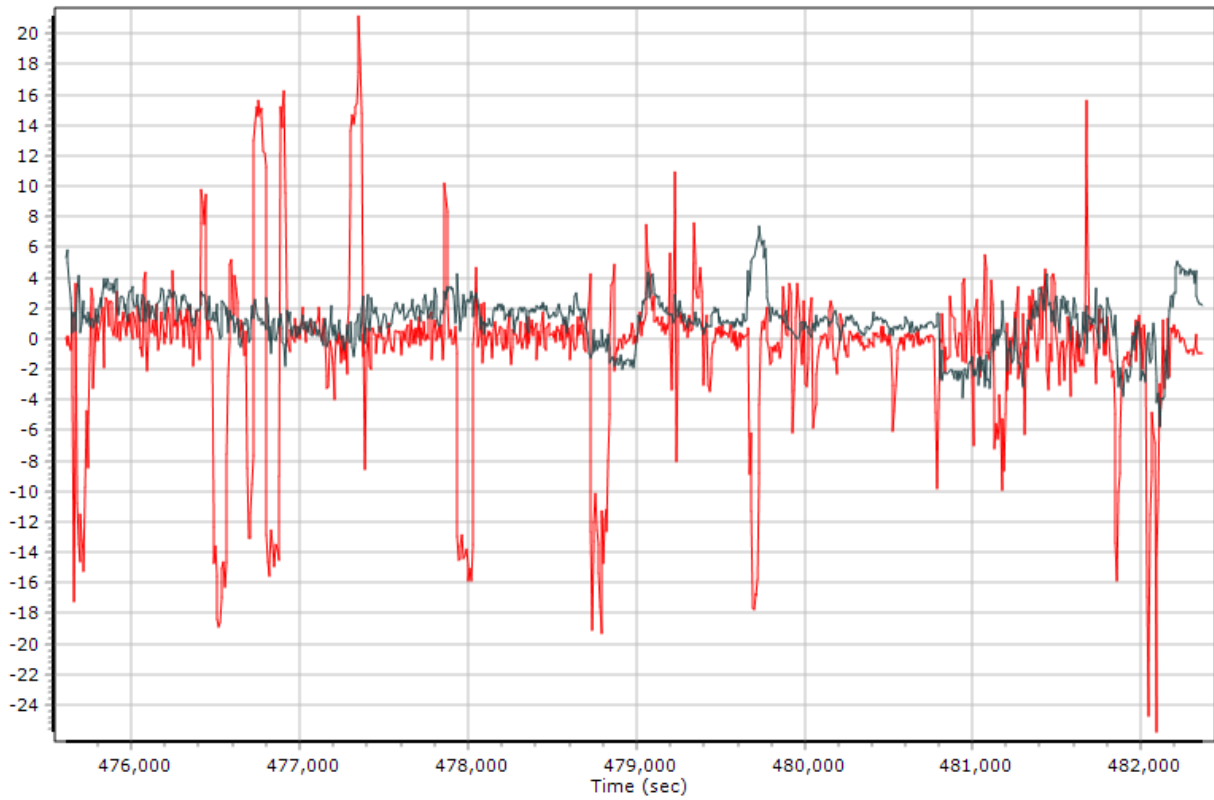
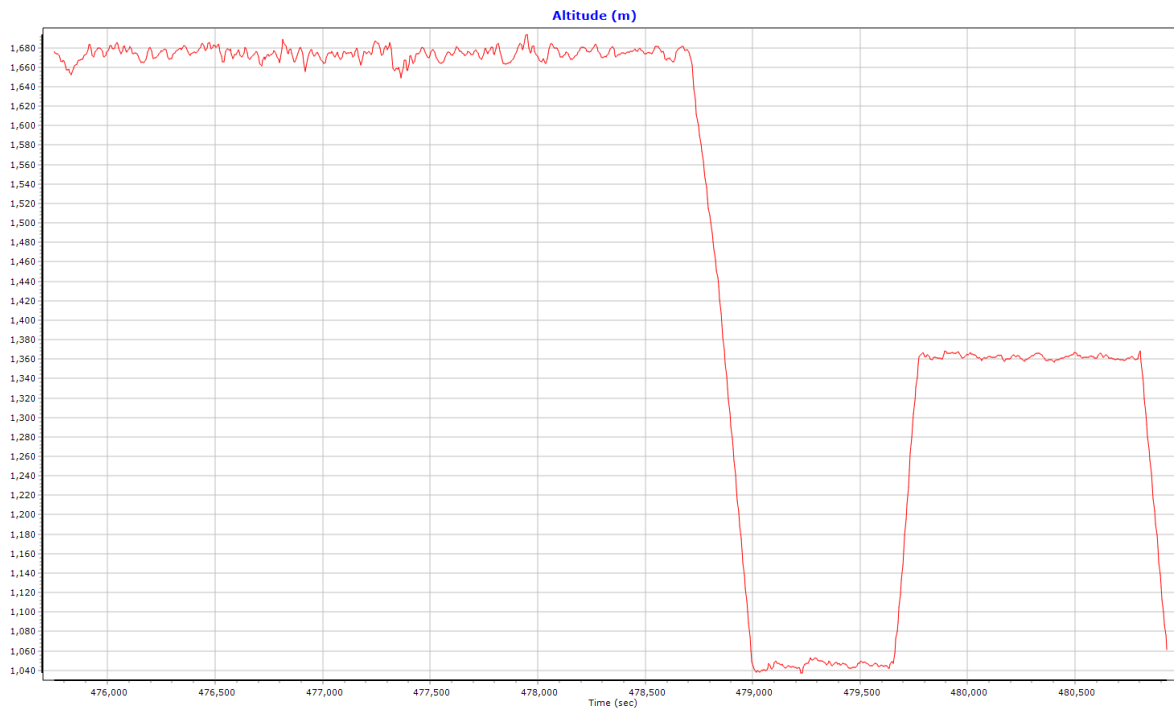




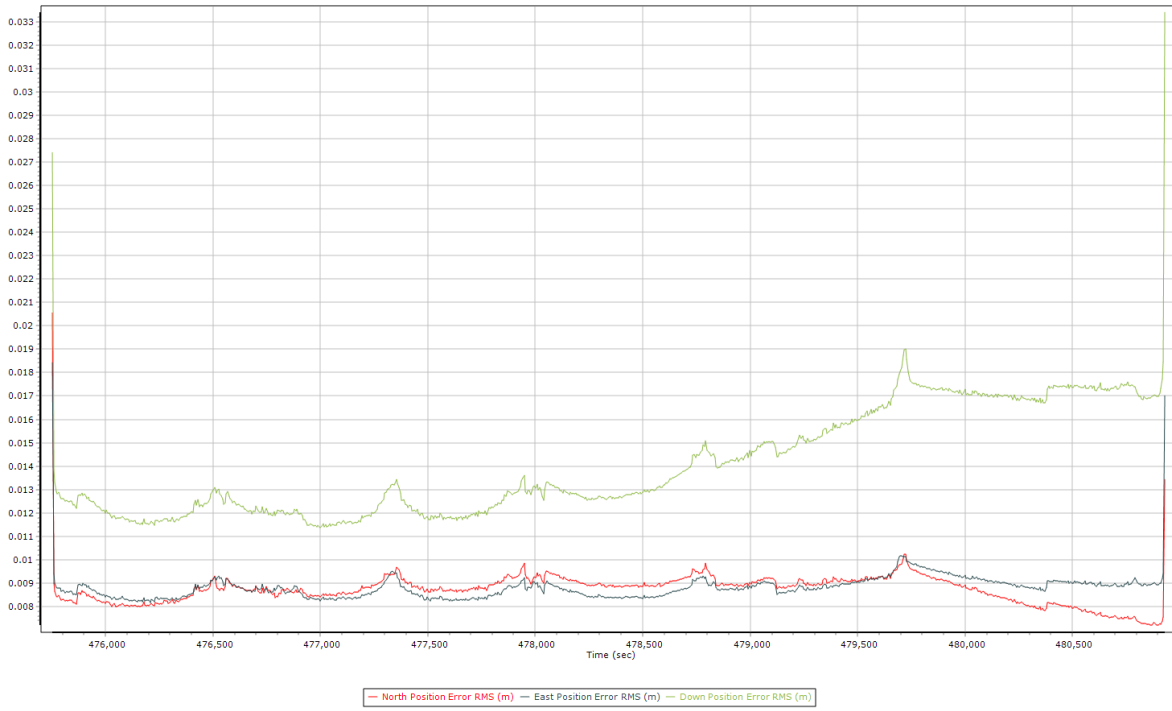
RBV19067A

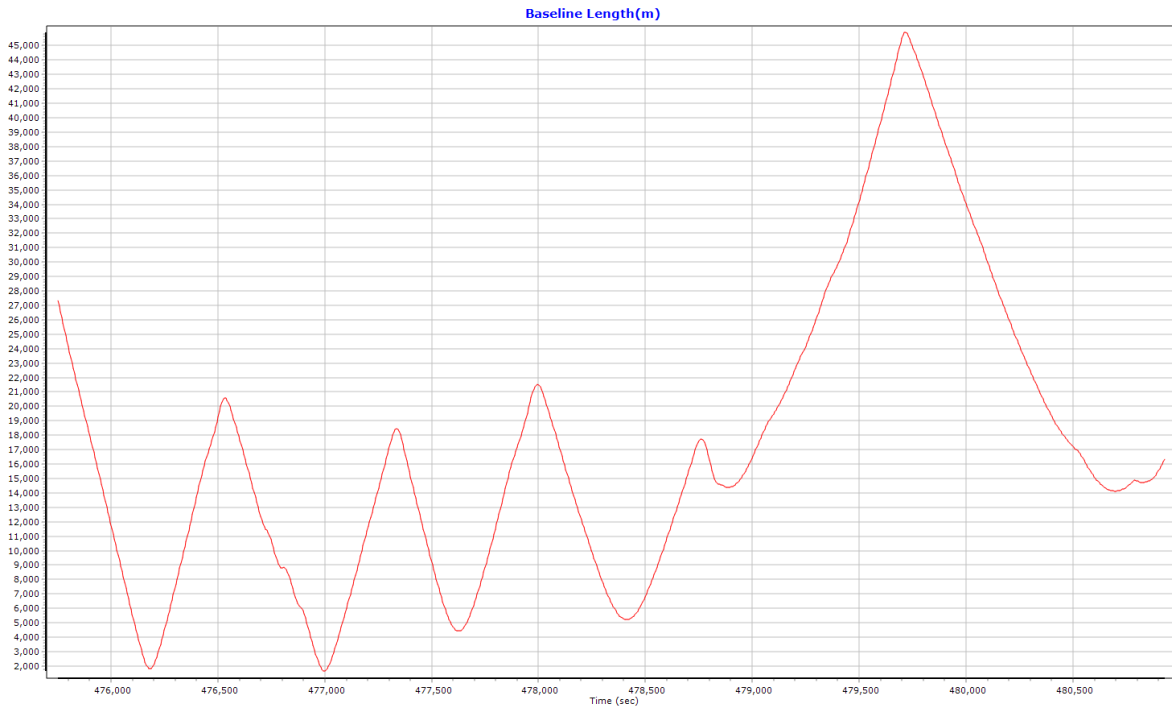
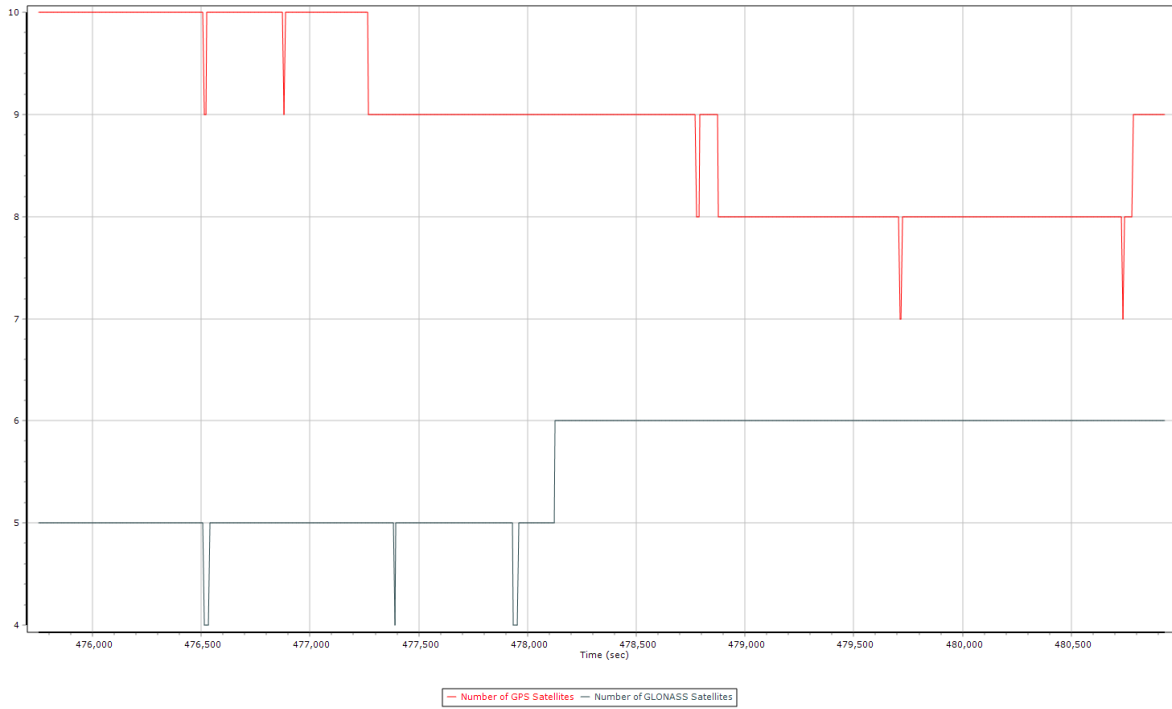


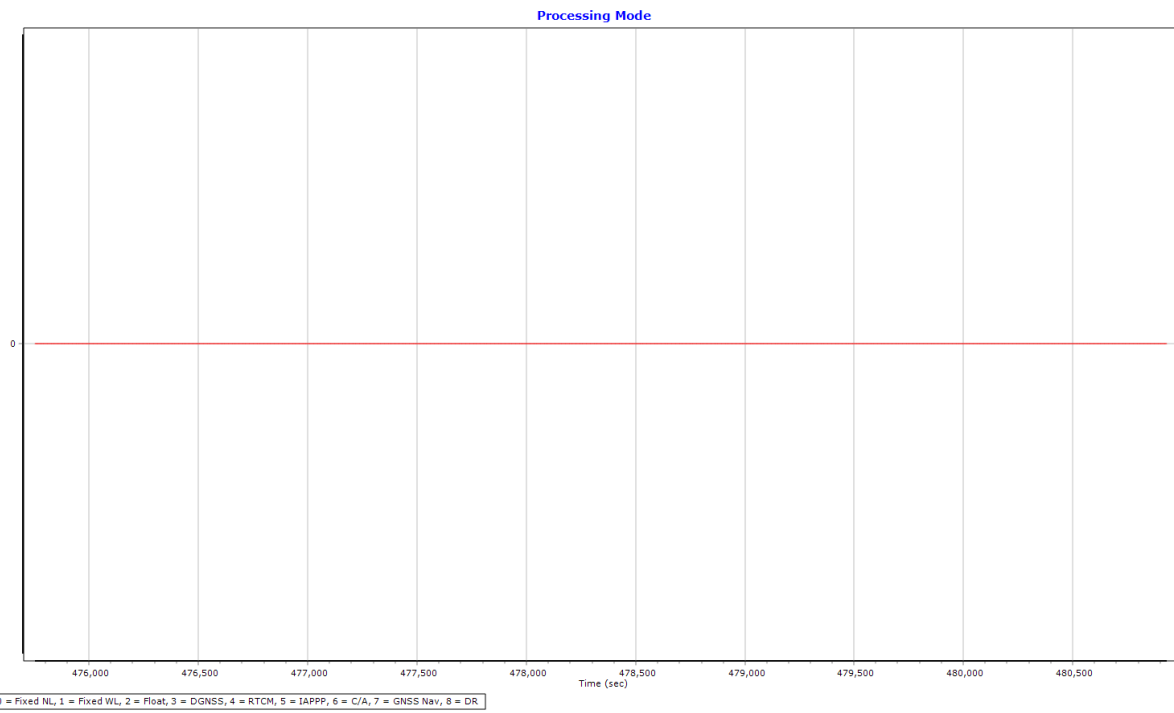
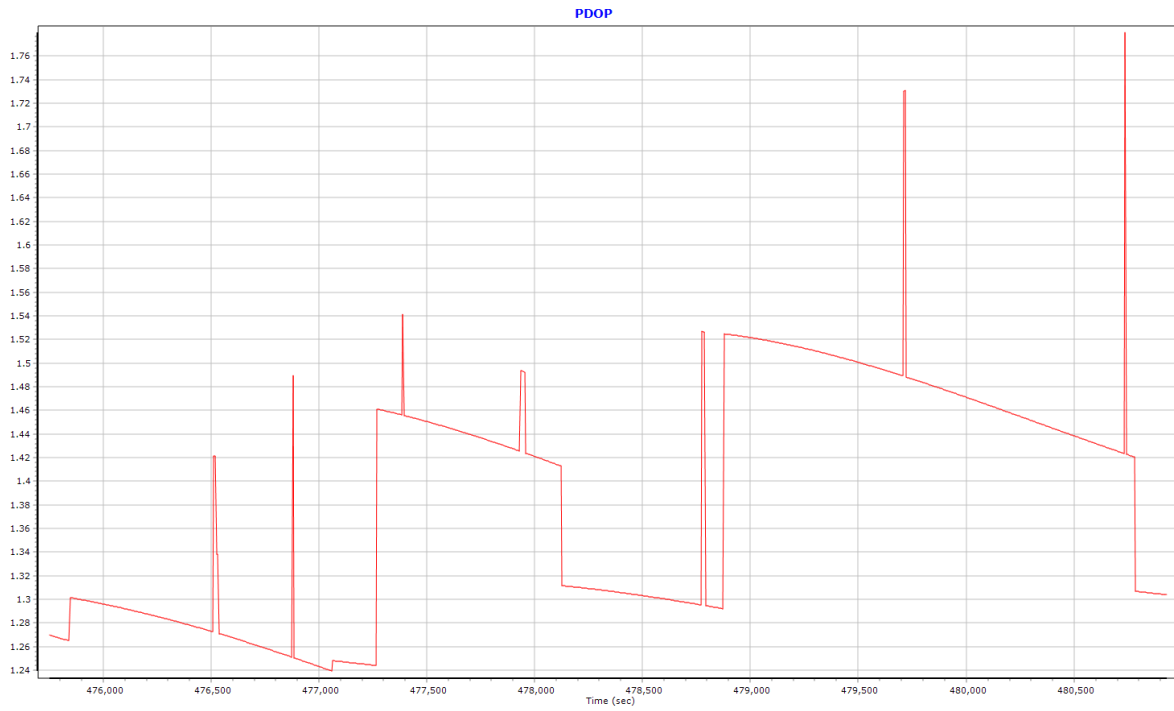




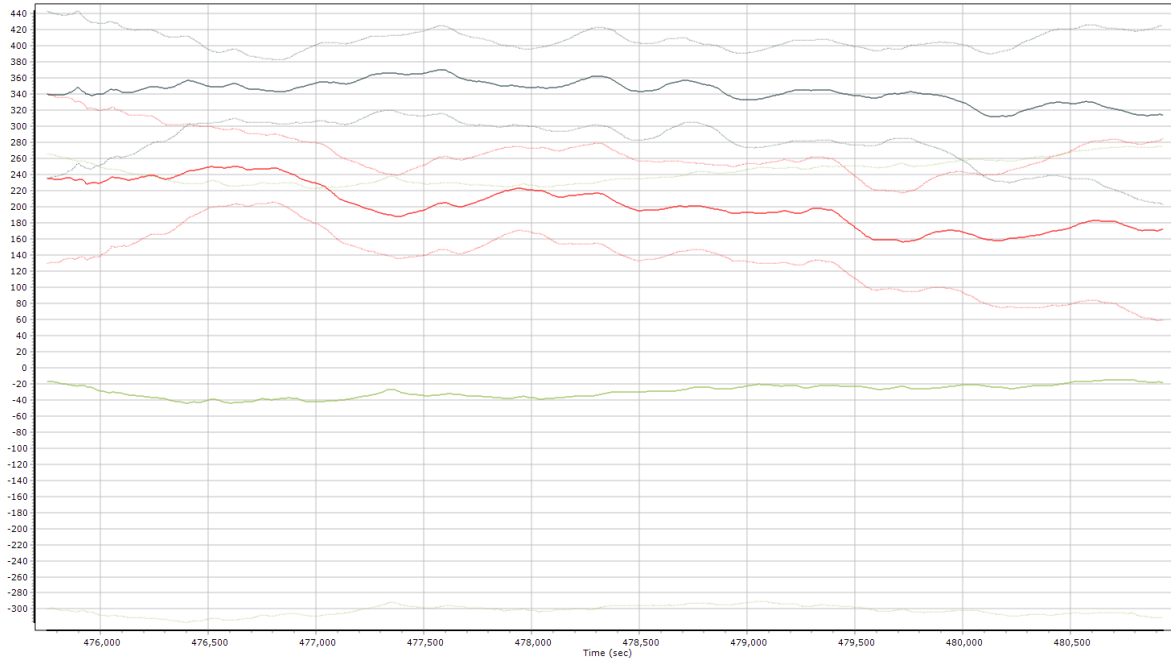
— Roll (deg) — Pitch (deg)



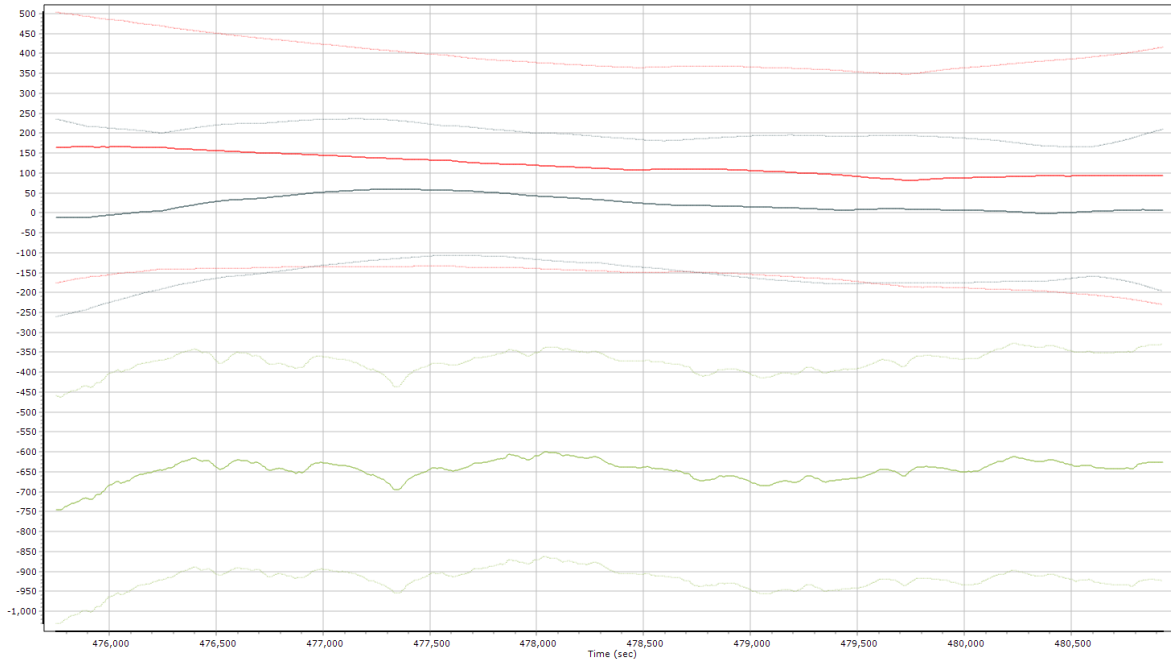




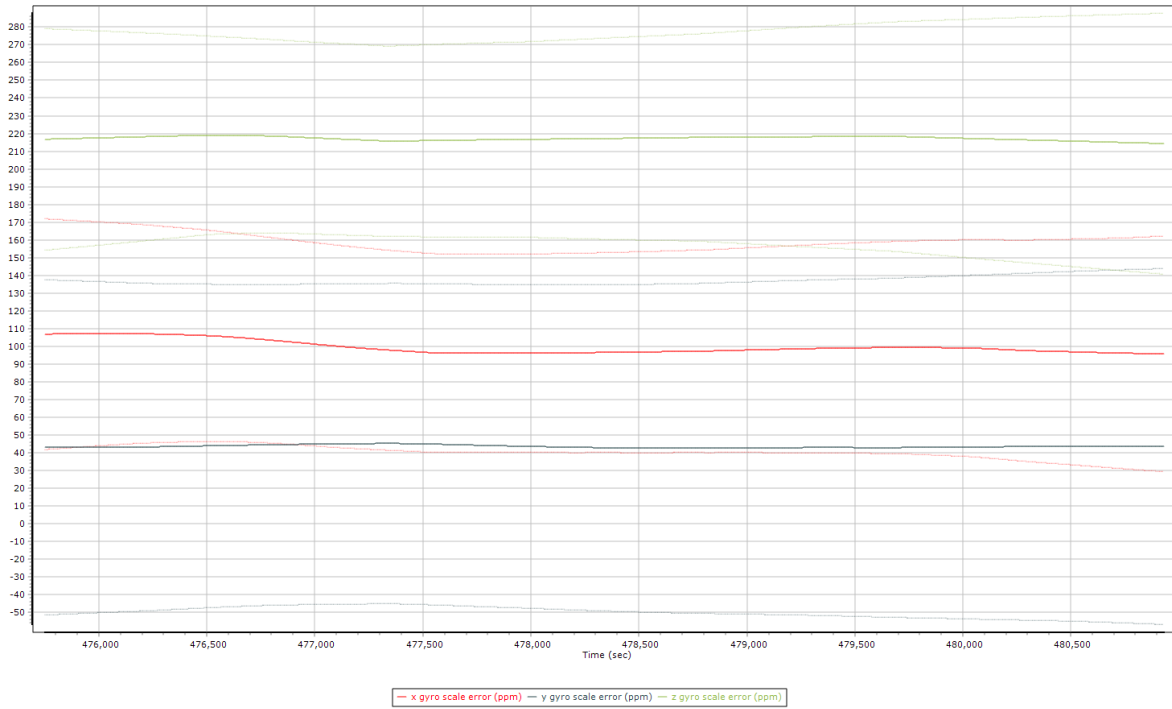
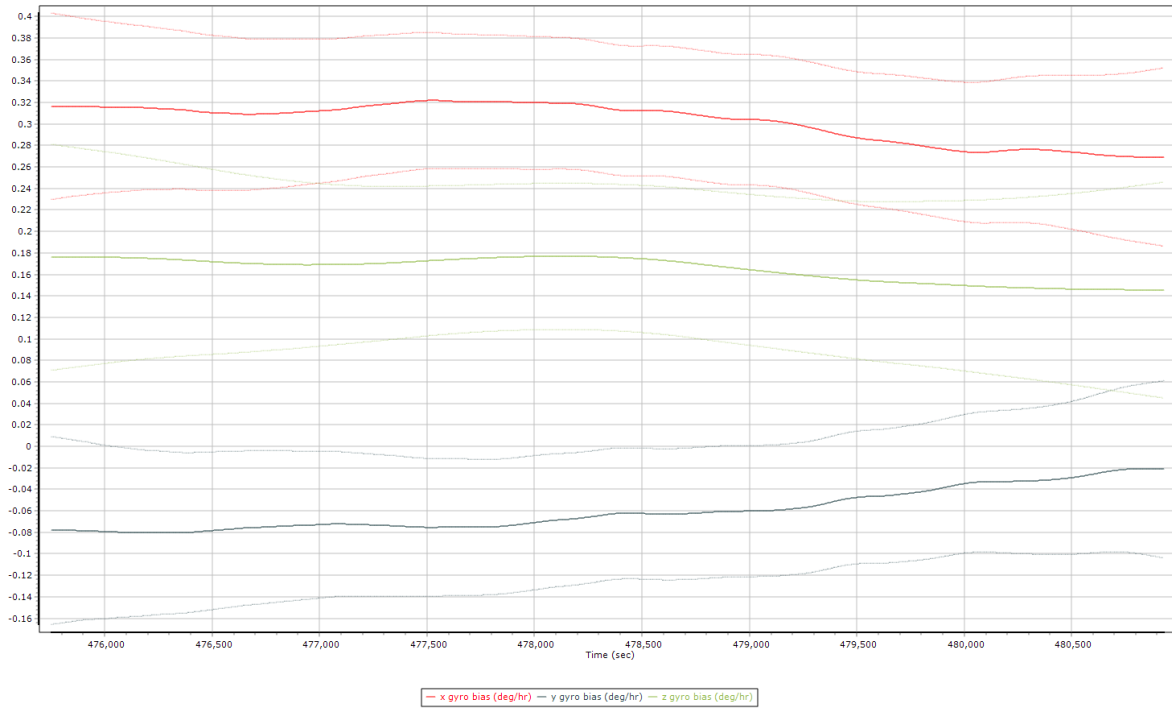
Sensor Errors



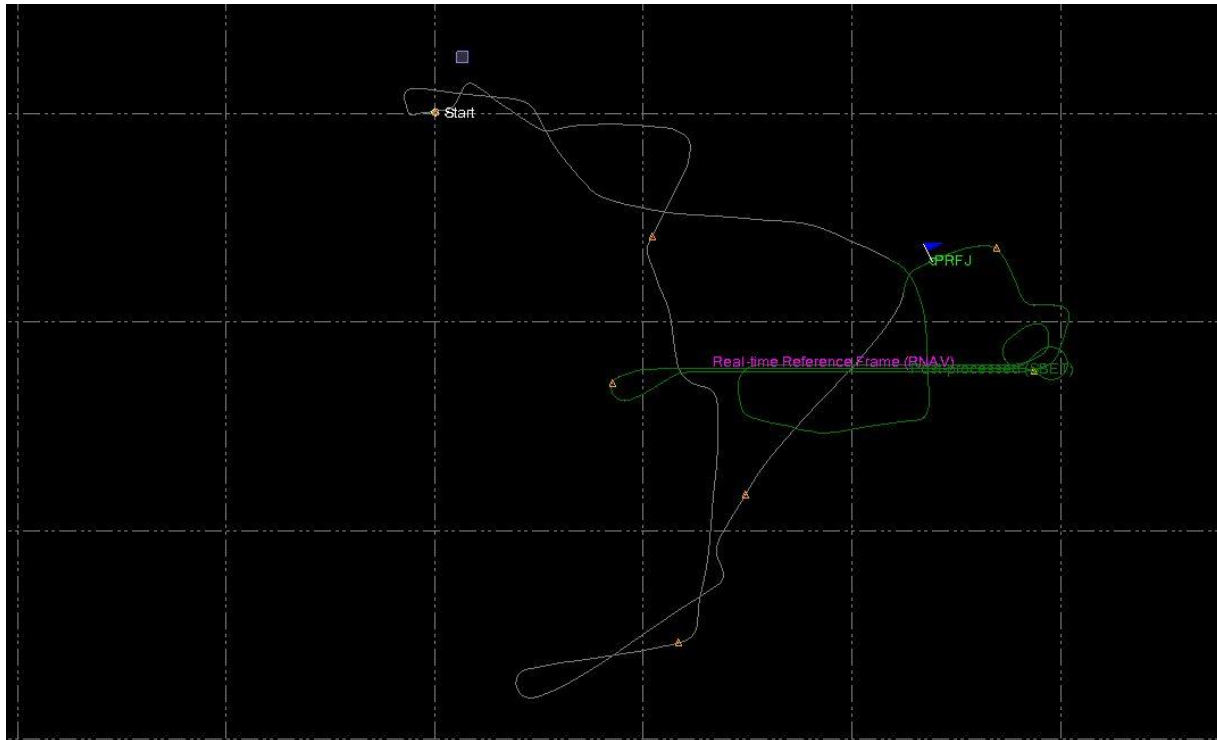
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



RBV19078A



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: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 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: 216774.258

End: 220325.877

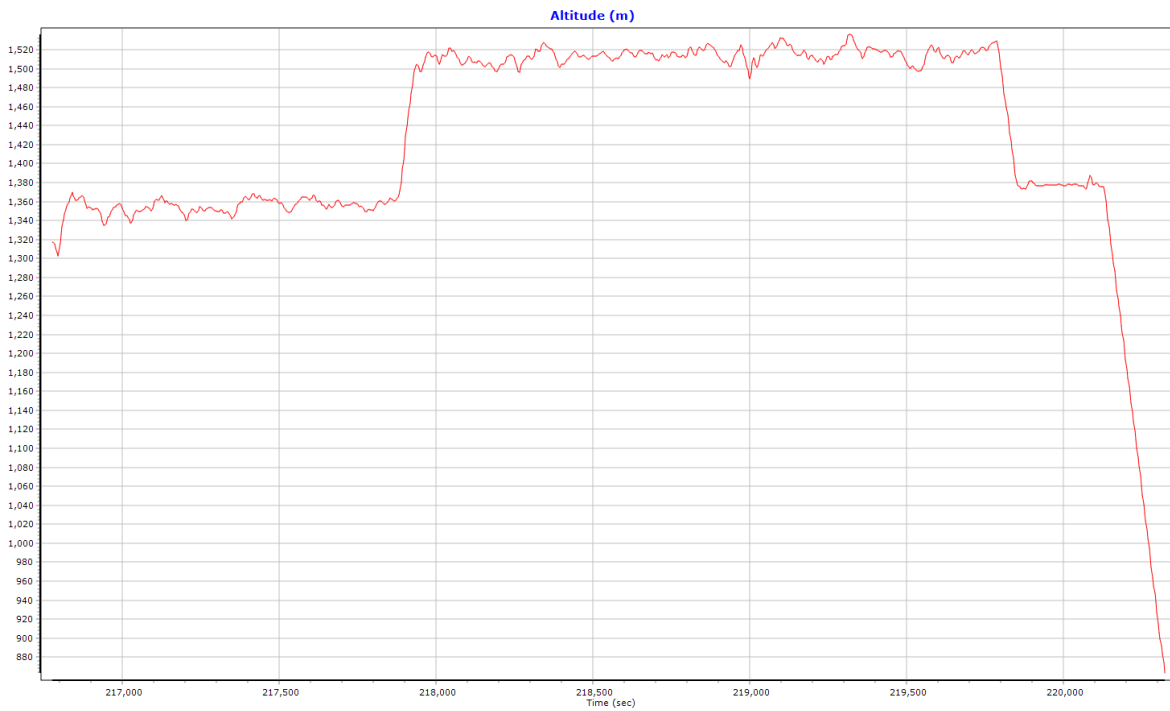
Entire time interval

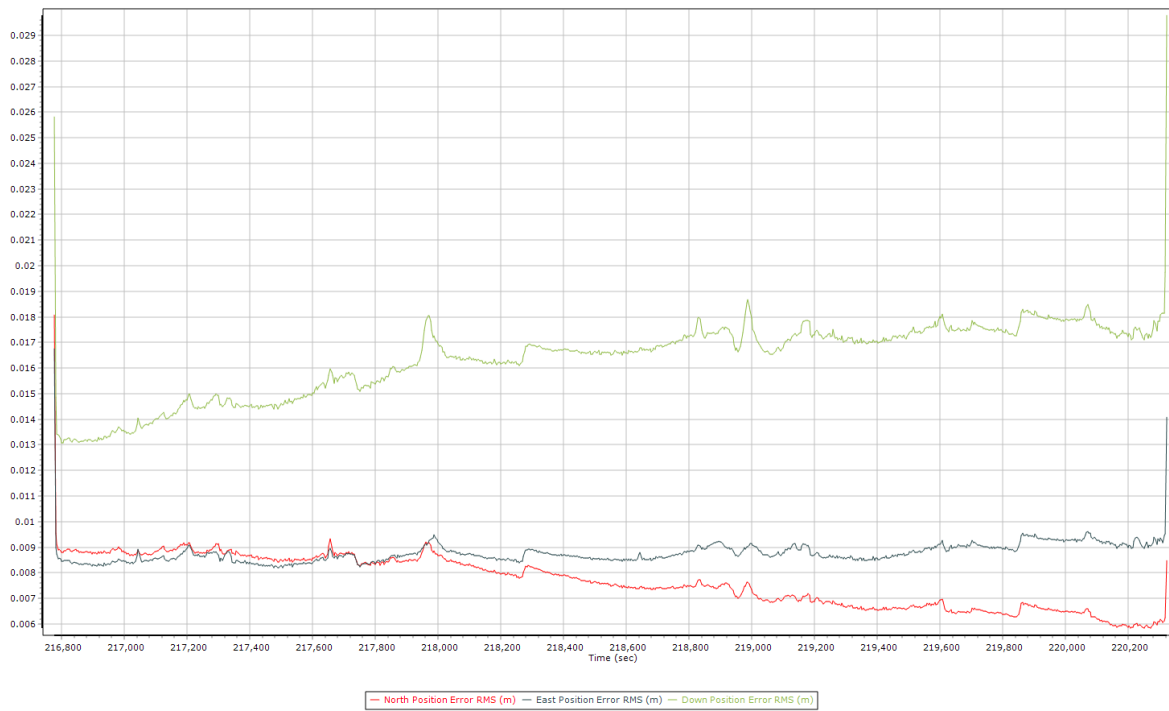
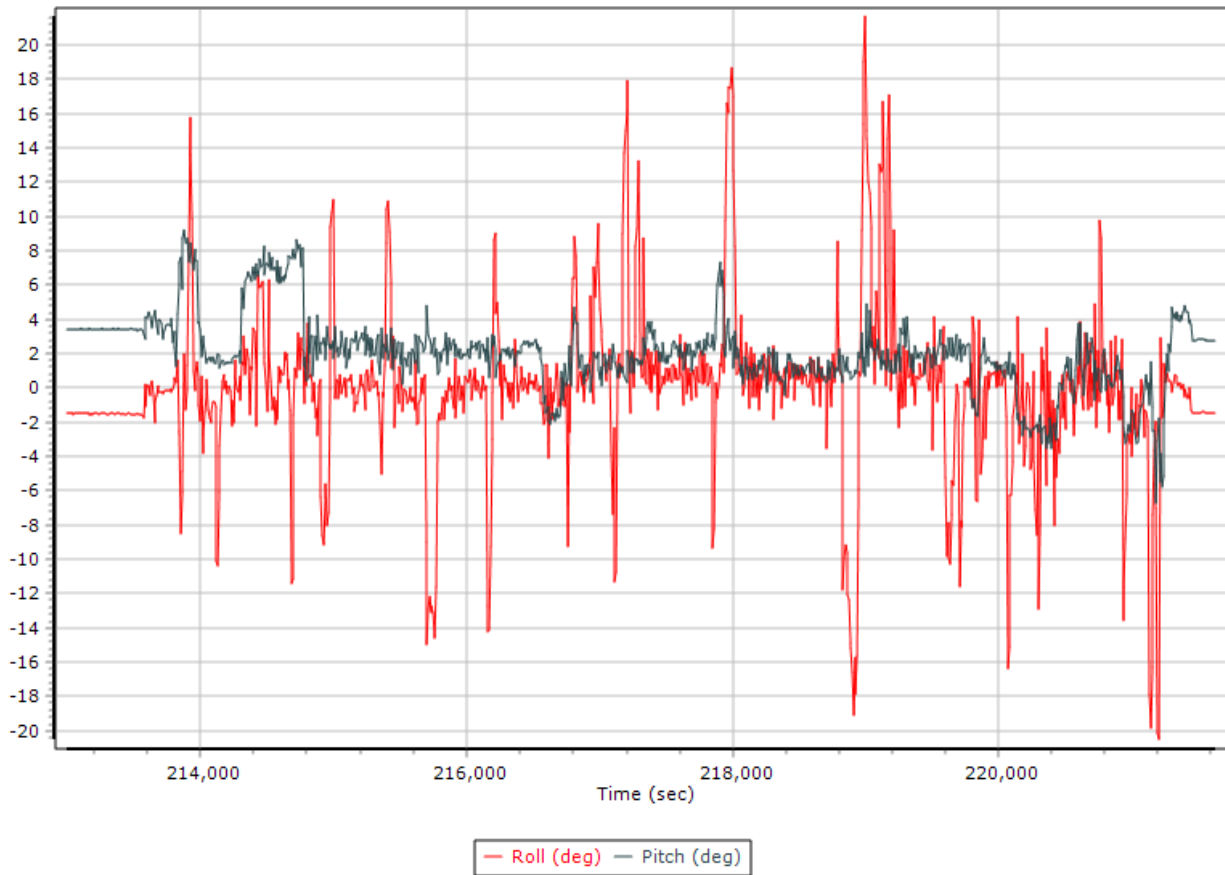
Seconds of start week

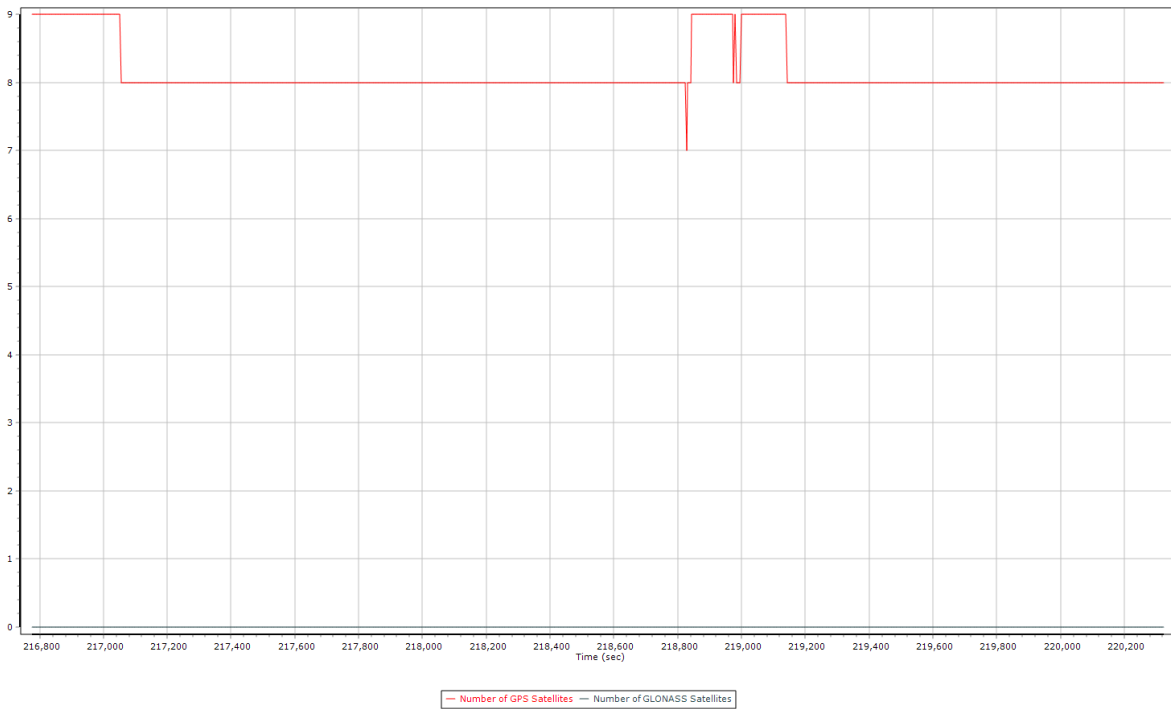
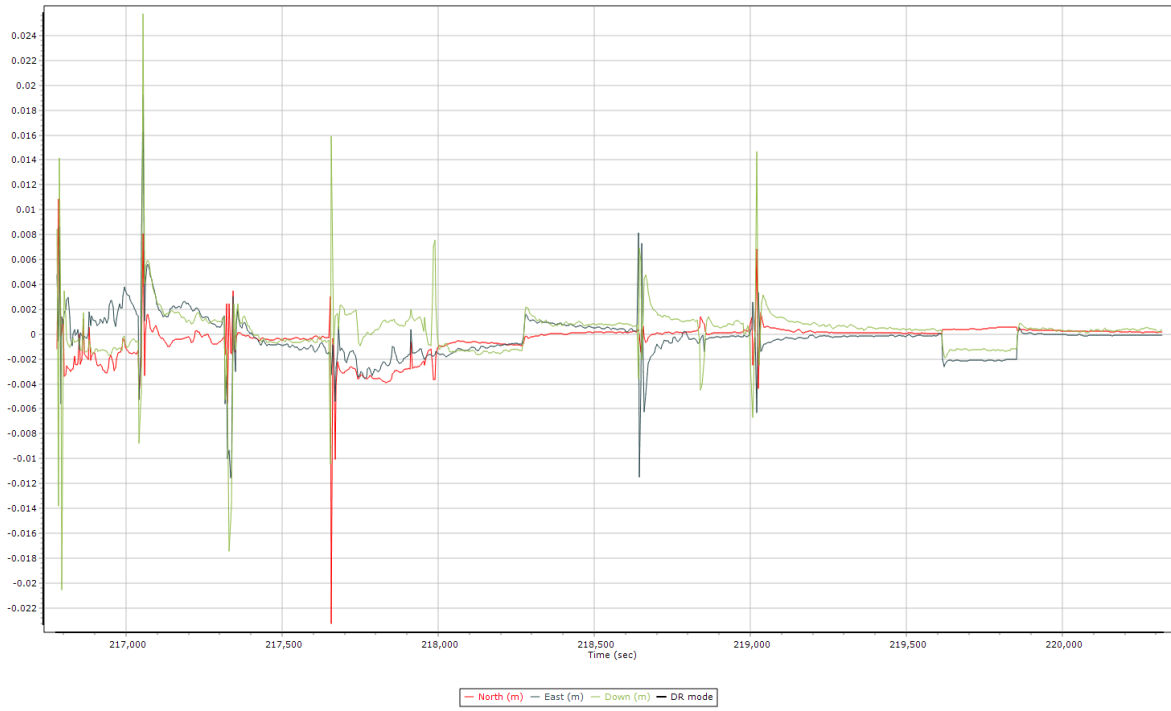
UTC Offset: 18.000

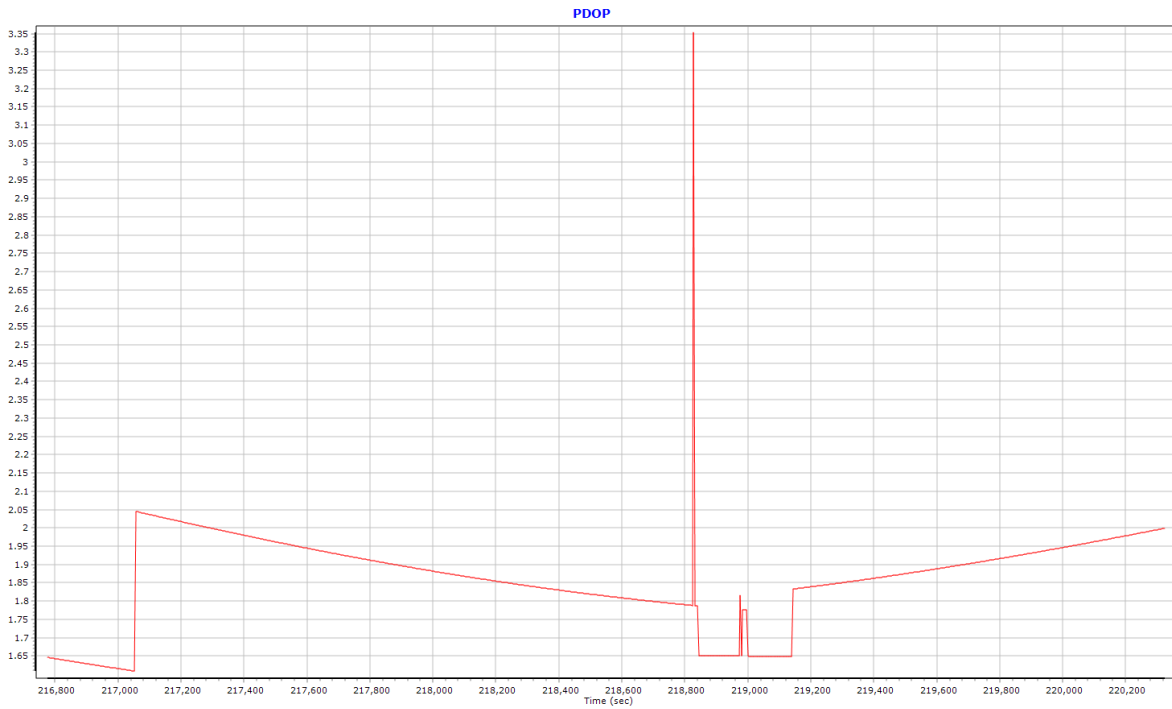
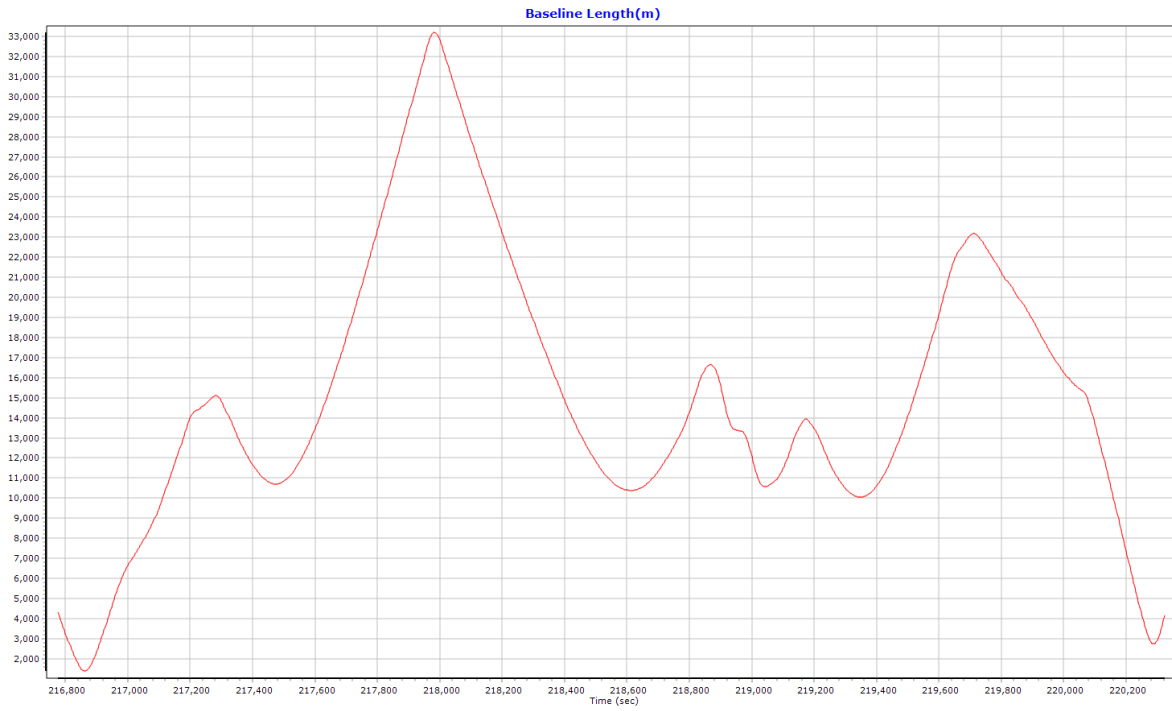
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

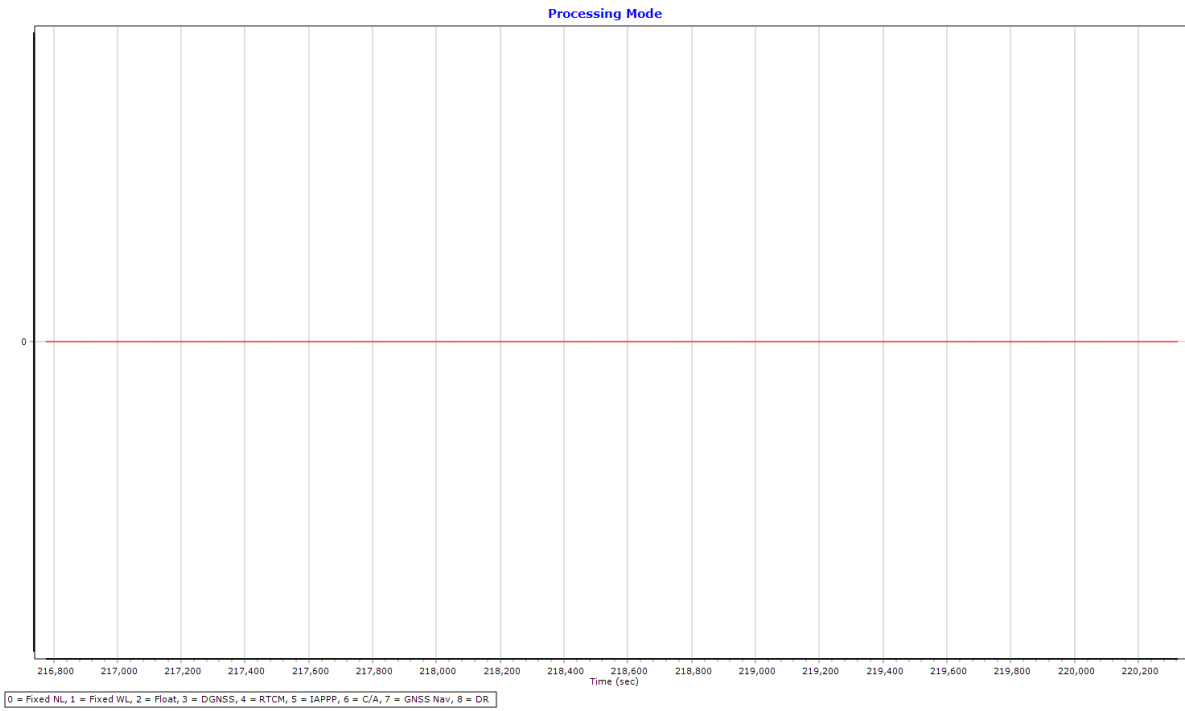
OK Cancel



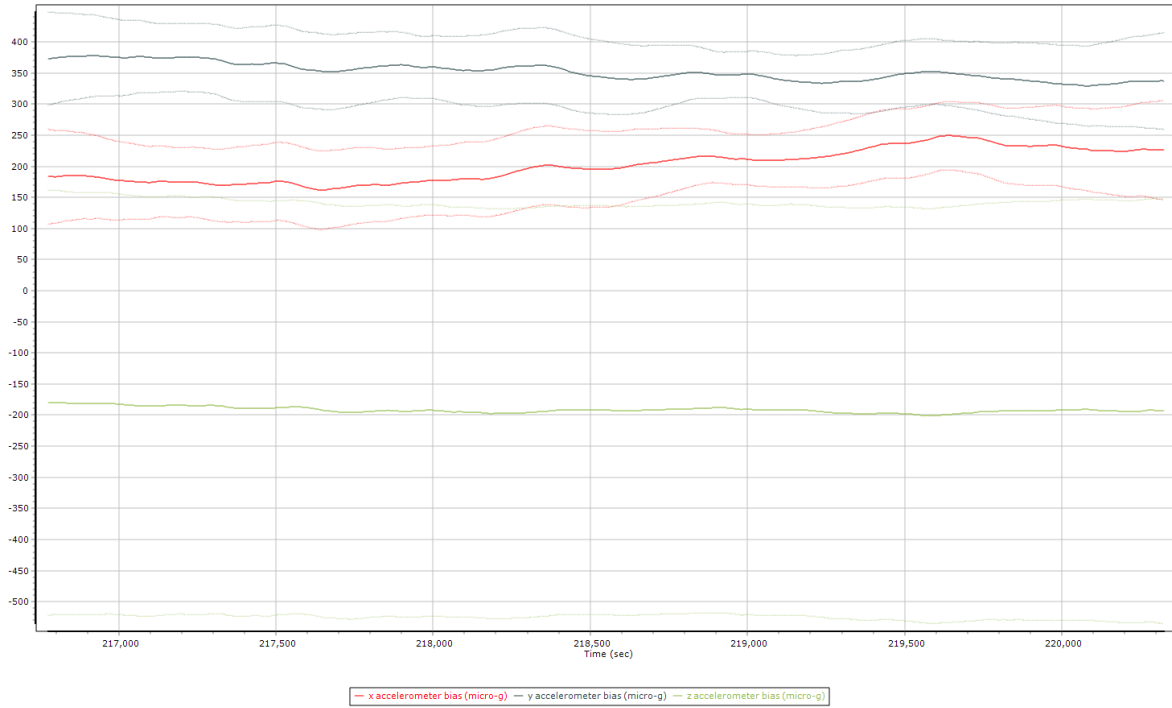


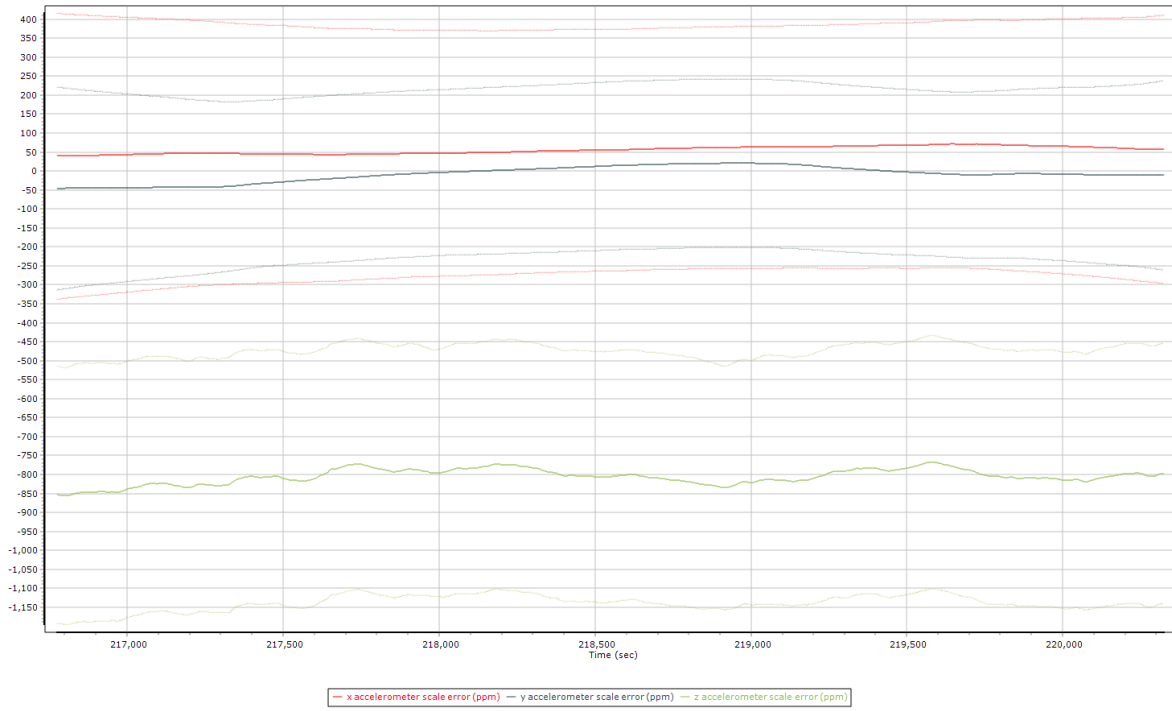






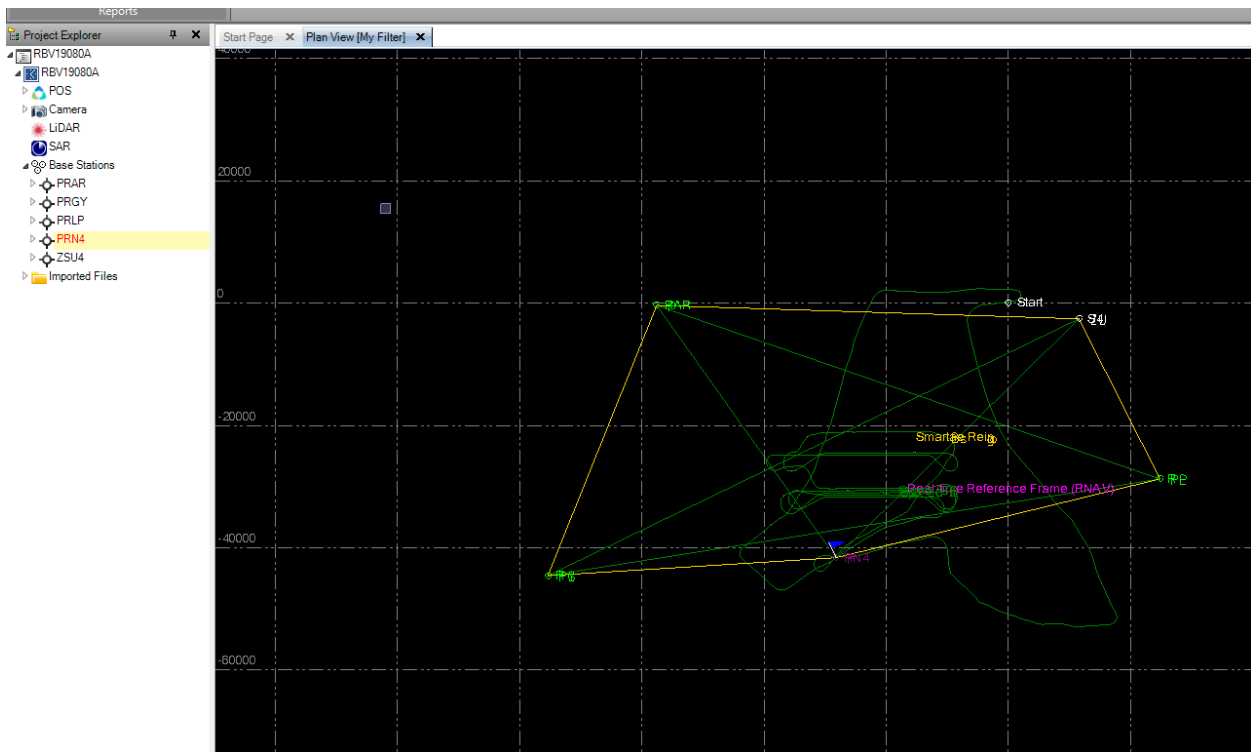
Sensor Errors







RBV19080A



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

X: 0.000 m
Y: 0.000 m
Z: 0.000 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: -0.024 m
Y: -0.001 m
Z: -0.742 m

Aircraft to Reference Mounting Angles

X: 0.000 deg
Y: 0.000 deg
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

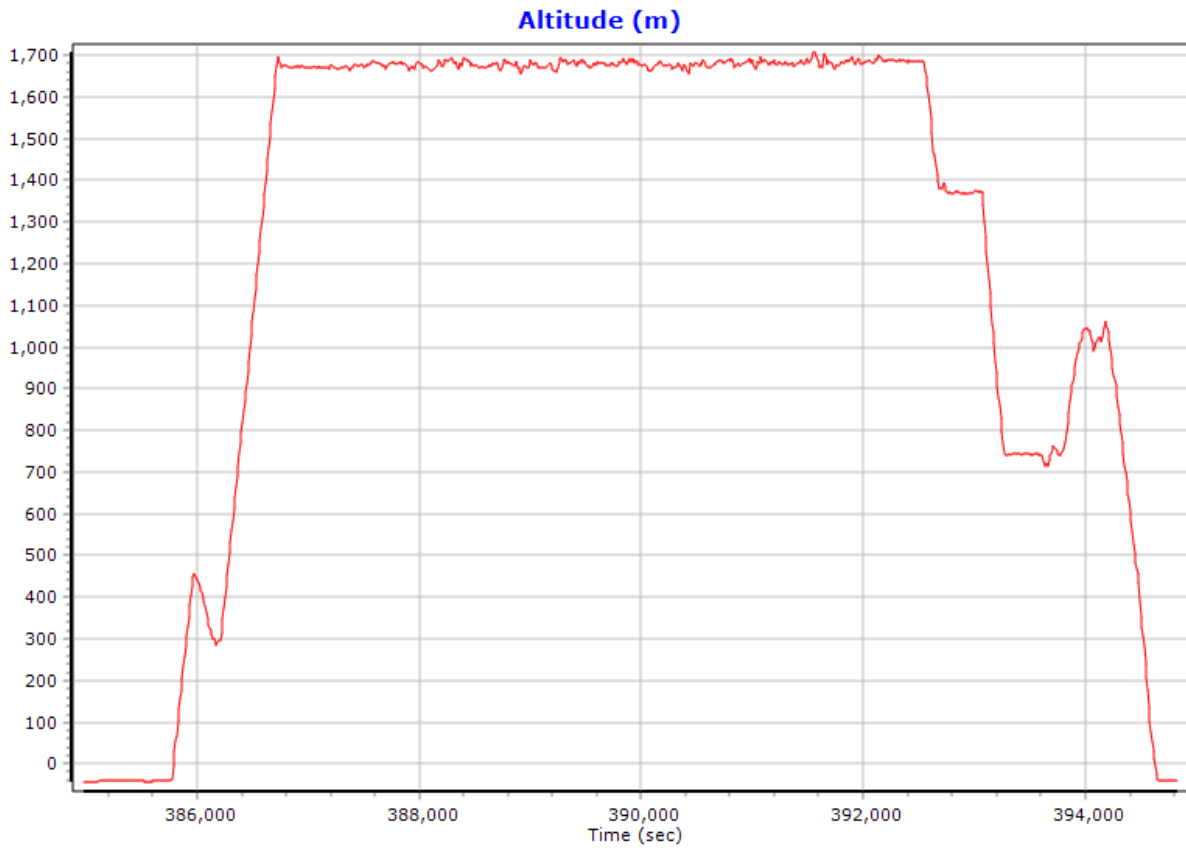
Start: 384975.000
End: 394838.000

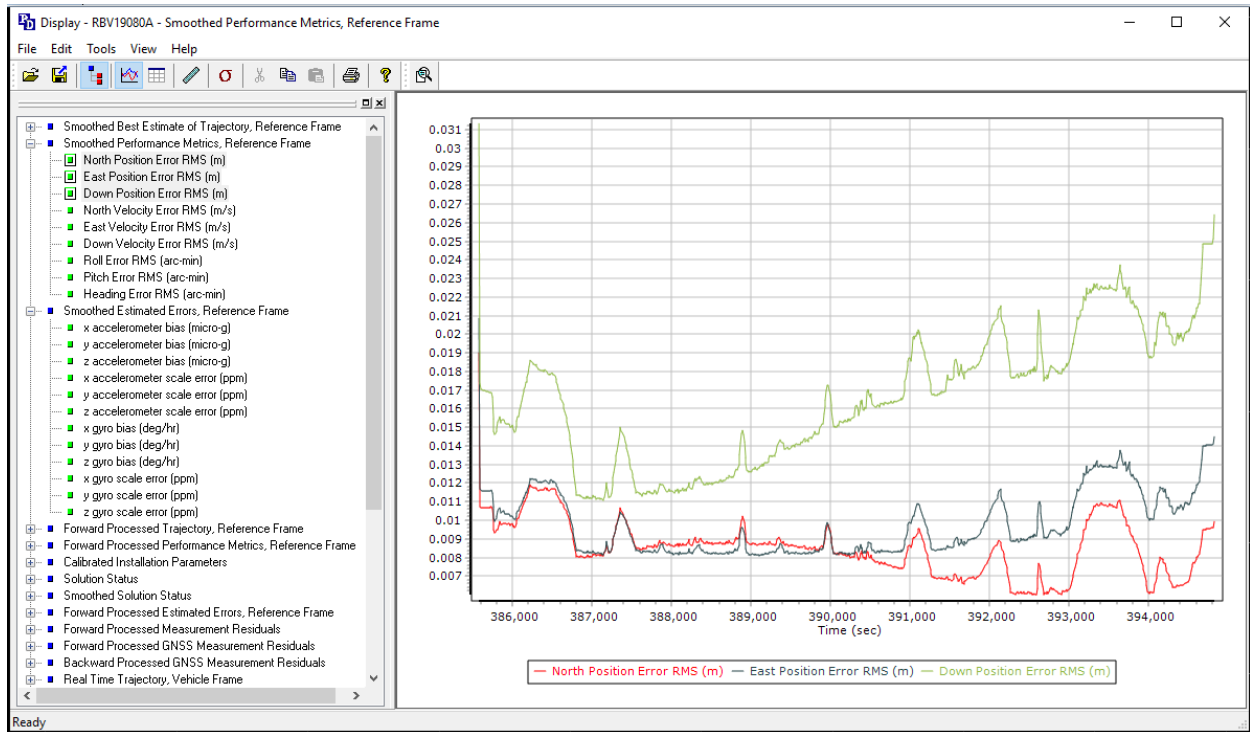
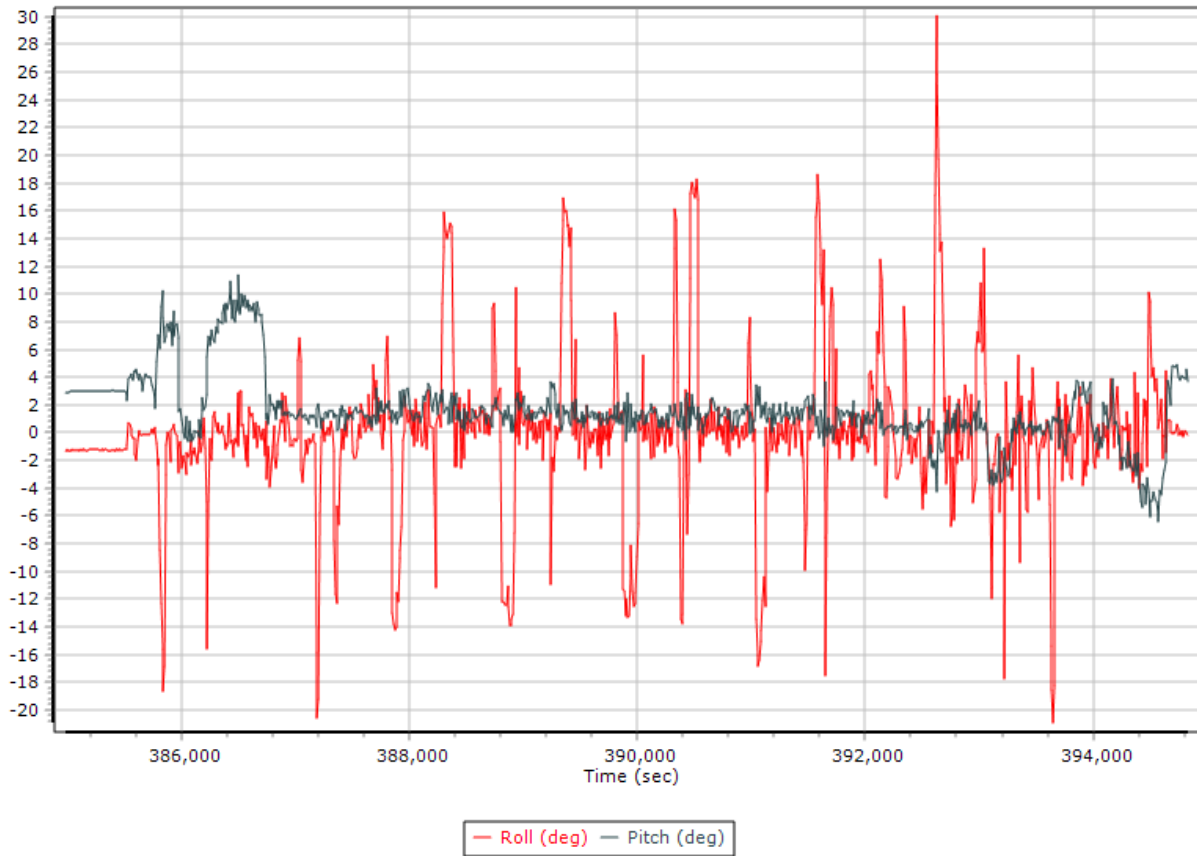
Entire time interval
 Seconds of start week

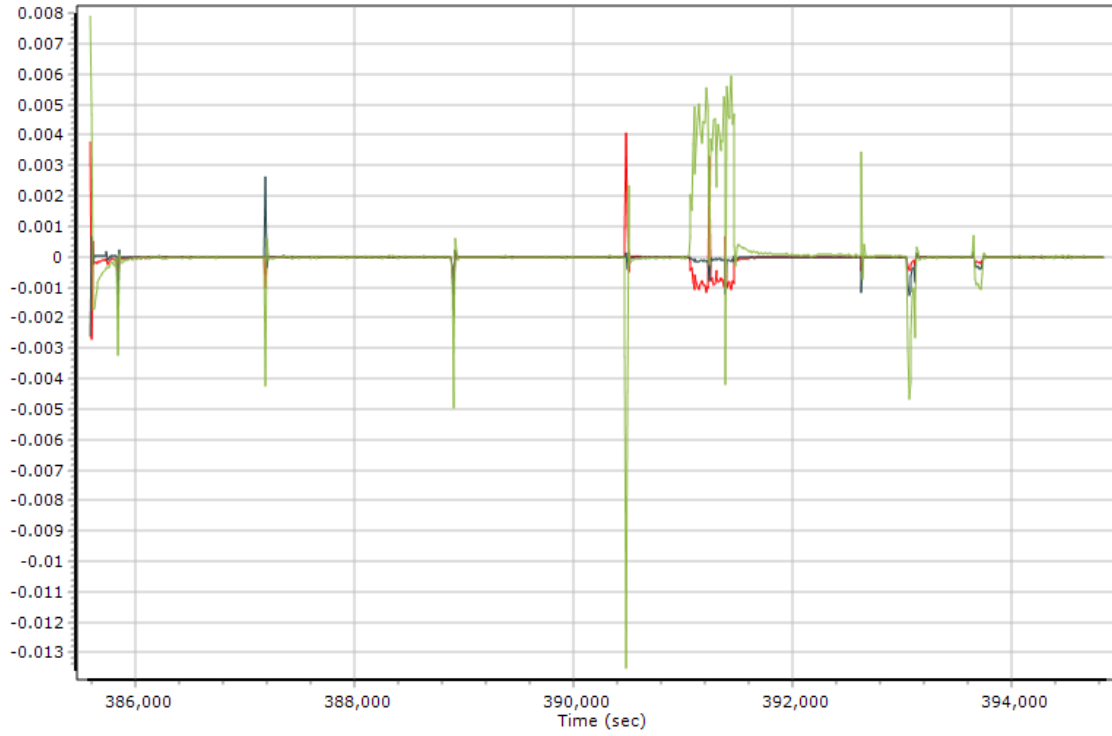
UTC Offset: 18.000

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

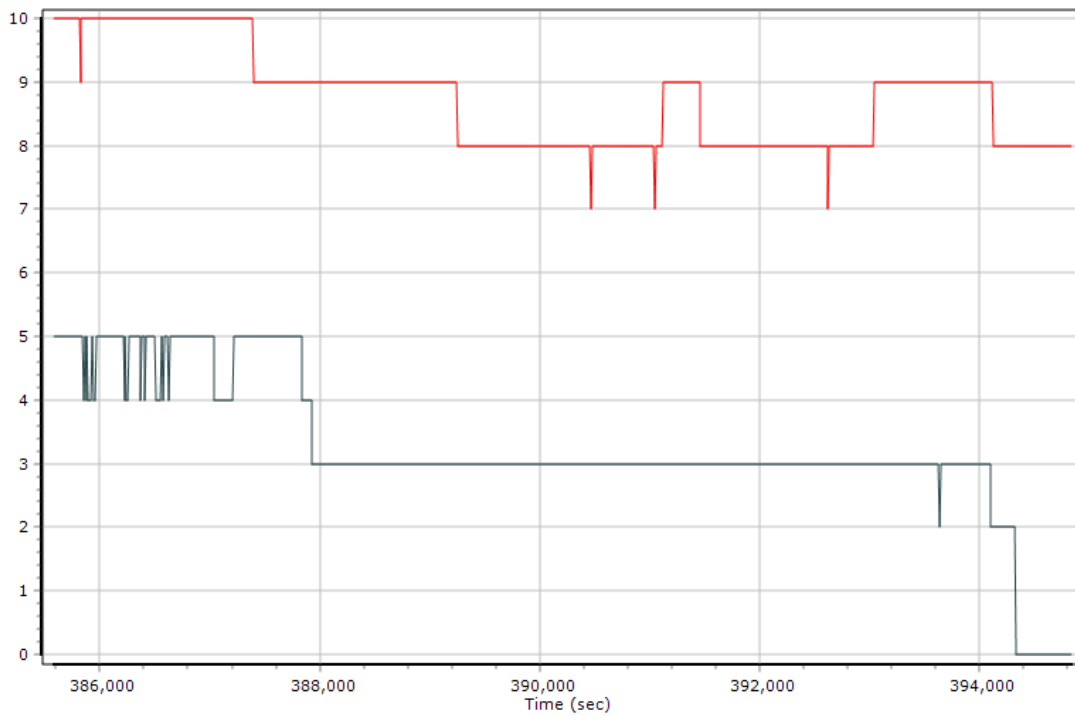
OK Cancel





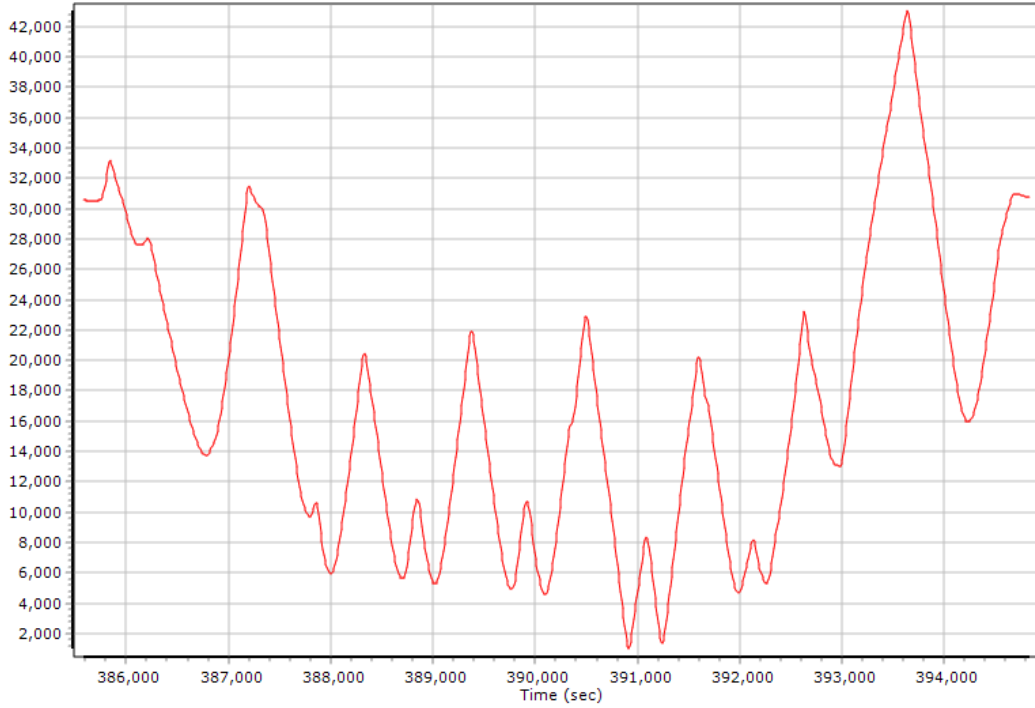


— North (m) — East (m) — Down (m) — DR mode

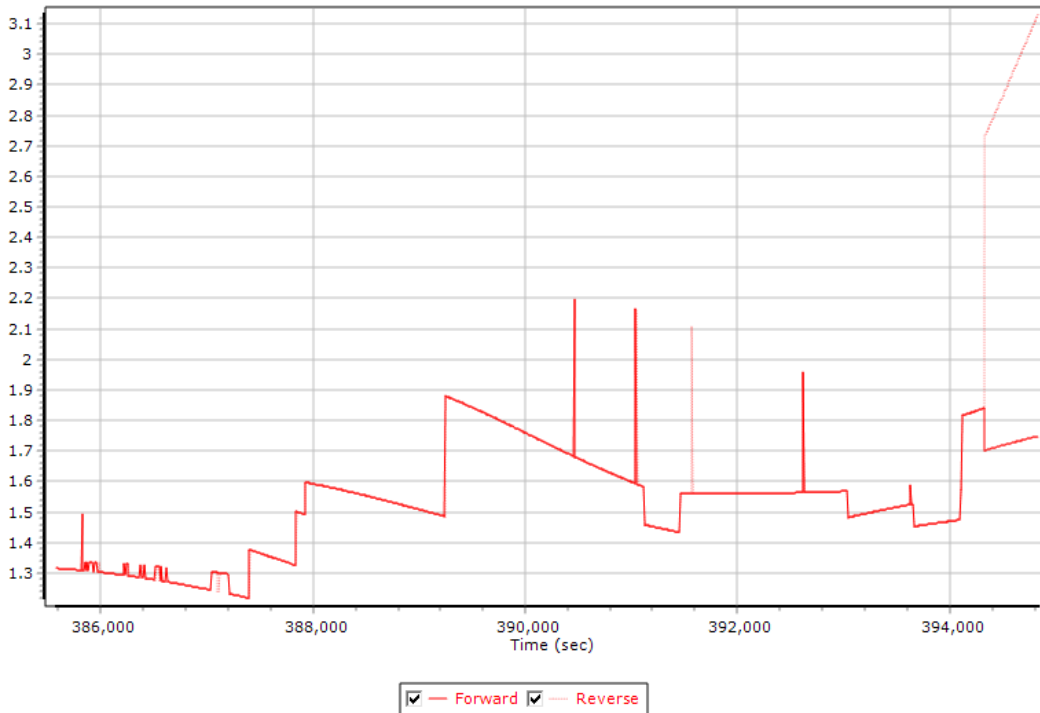


— Number of GPS Satellites — Number of GLONASS Satellites

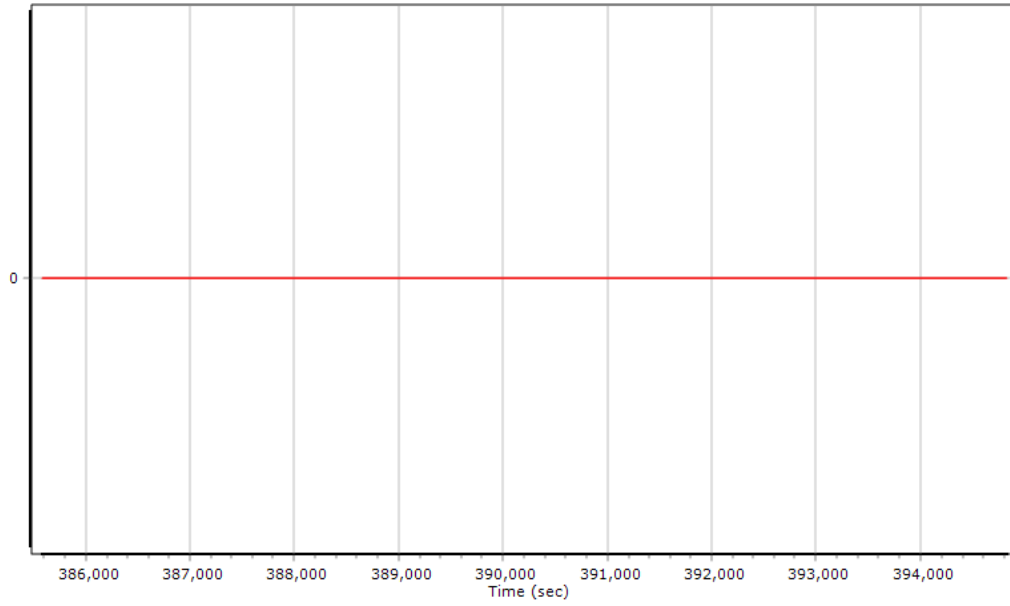
Baseline Length(m)



PDOP



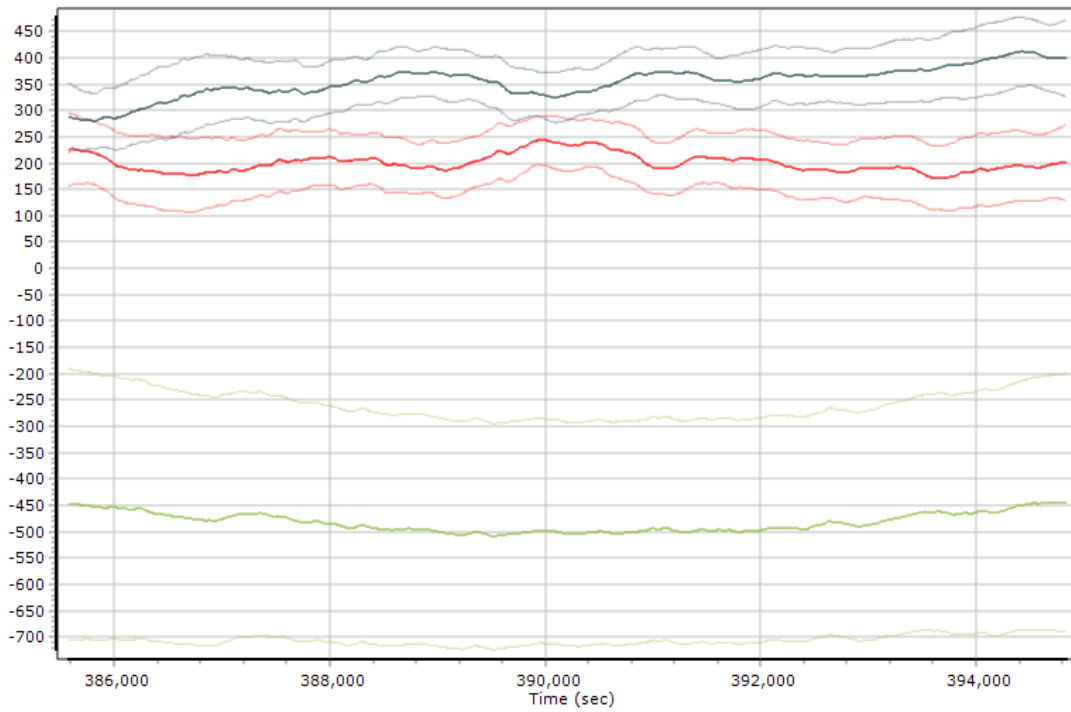
Processing Mode



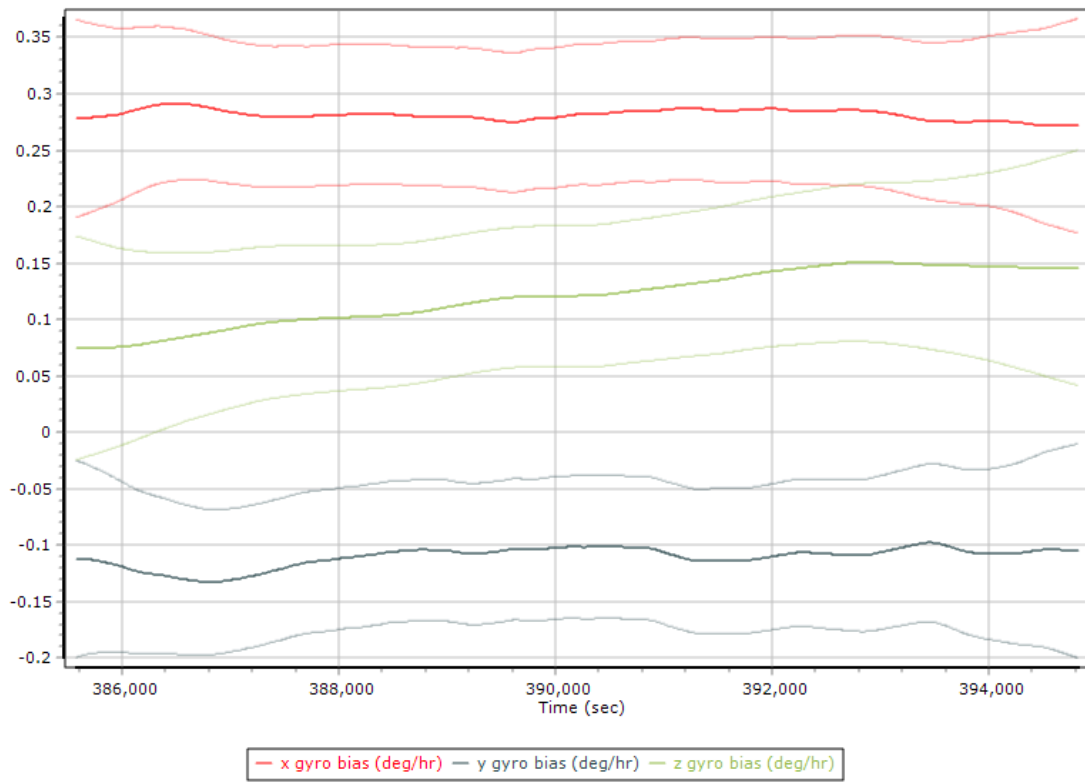
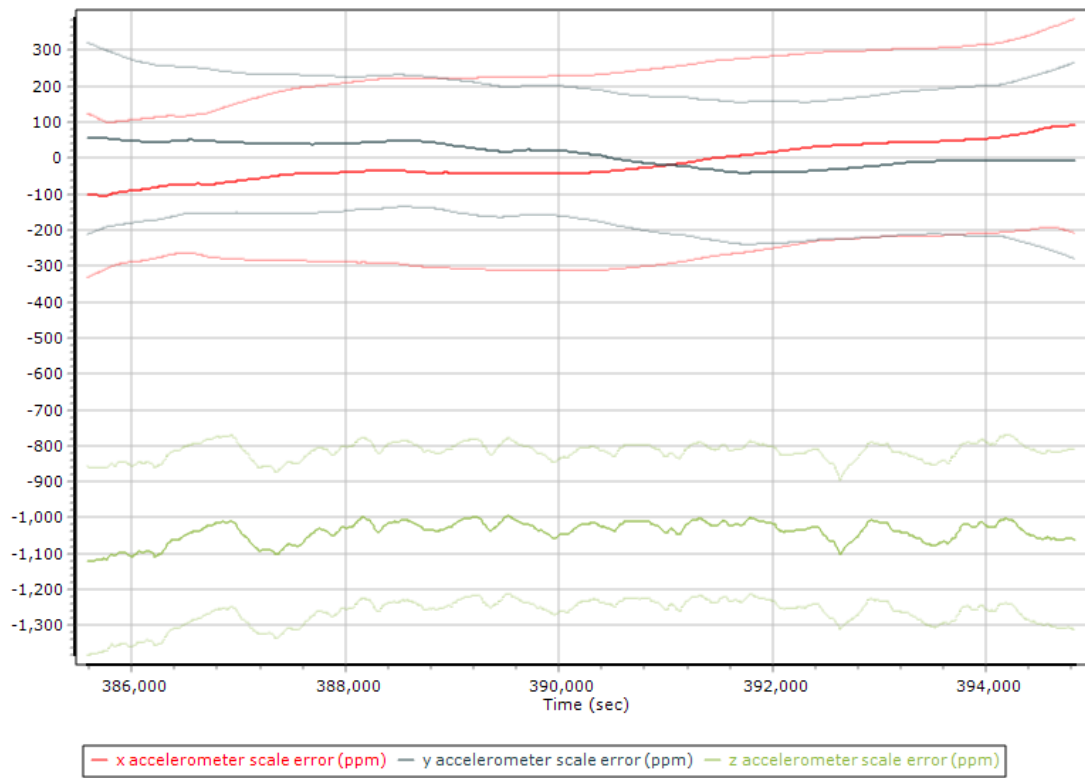
Forward Reverse

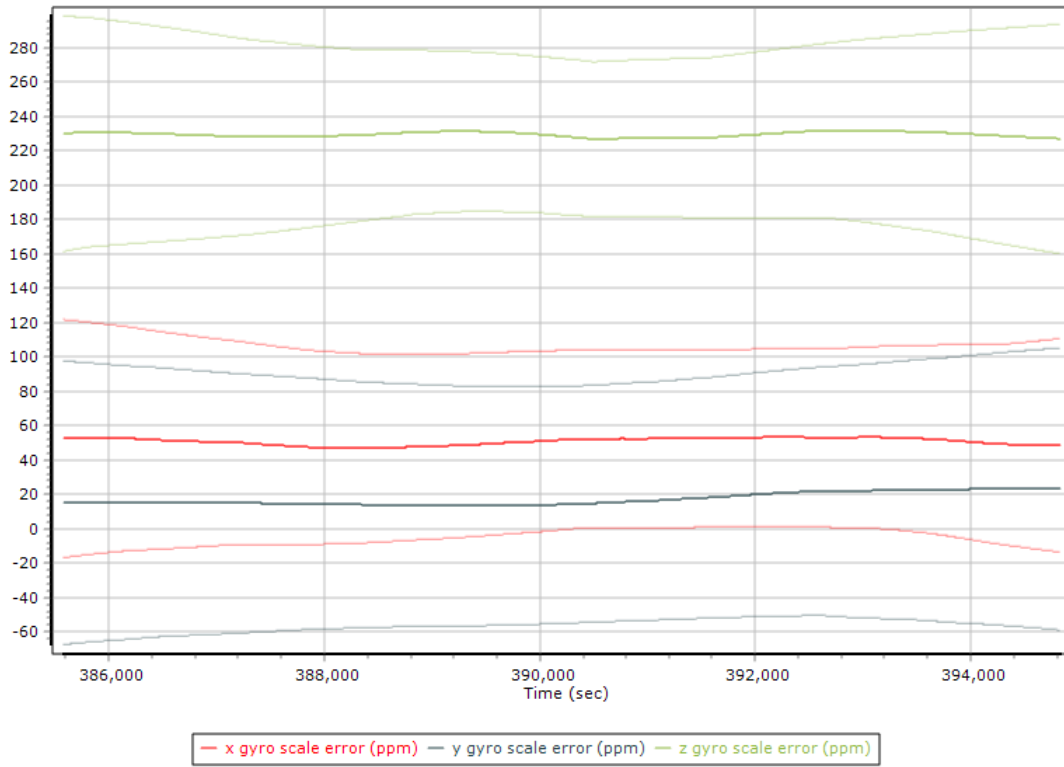
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors

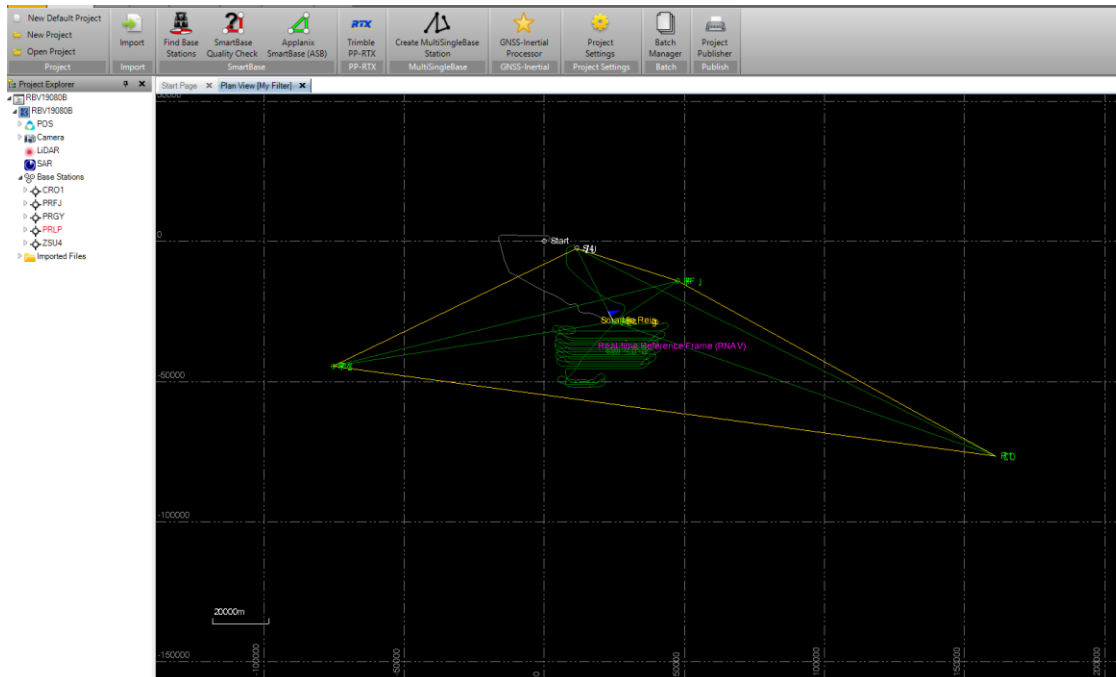


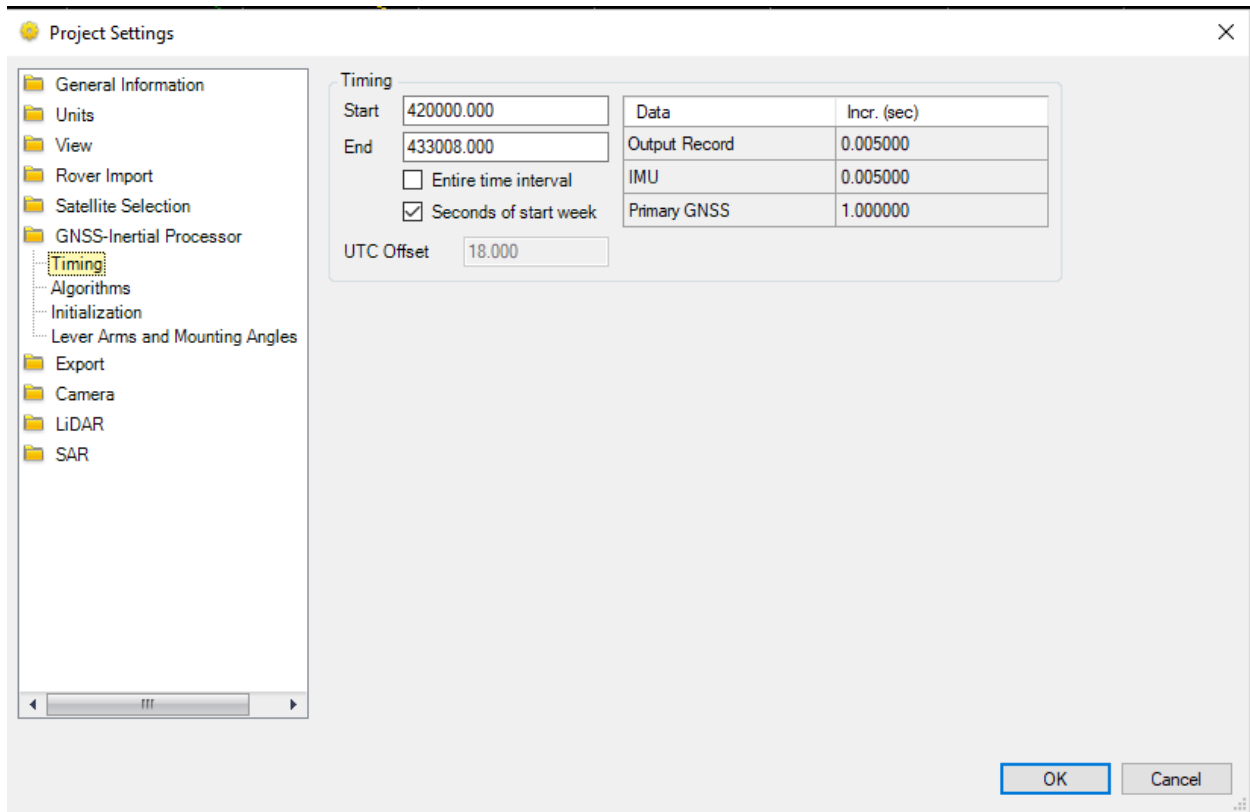
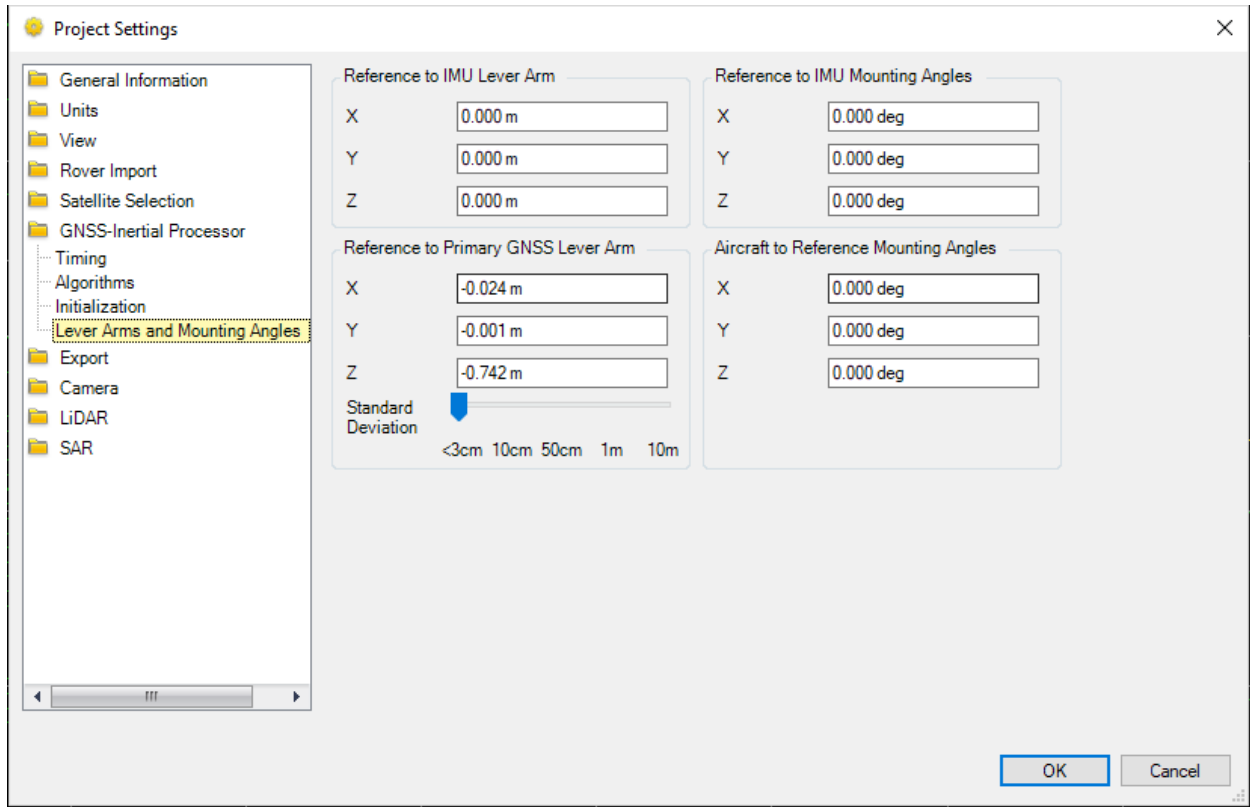
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)

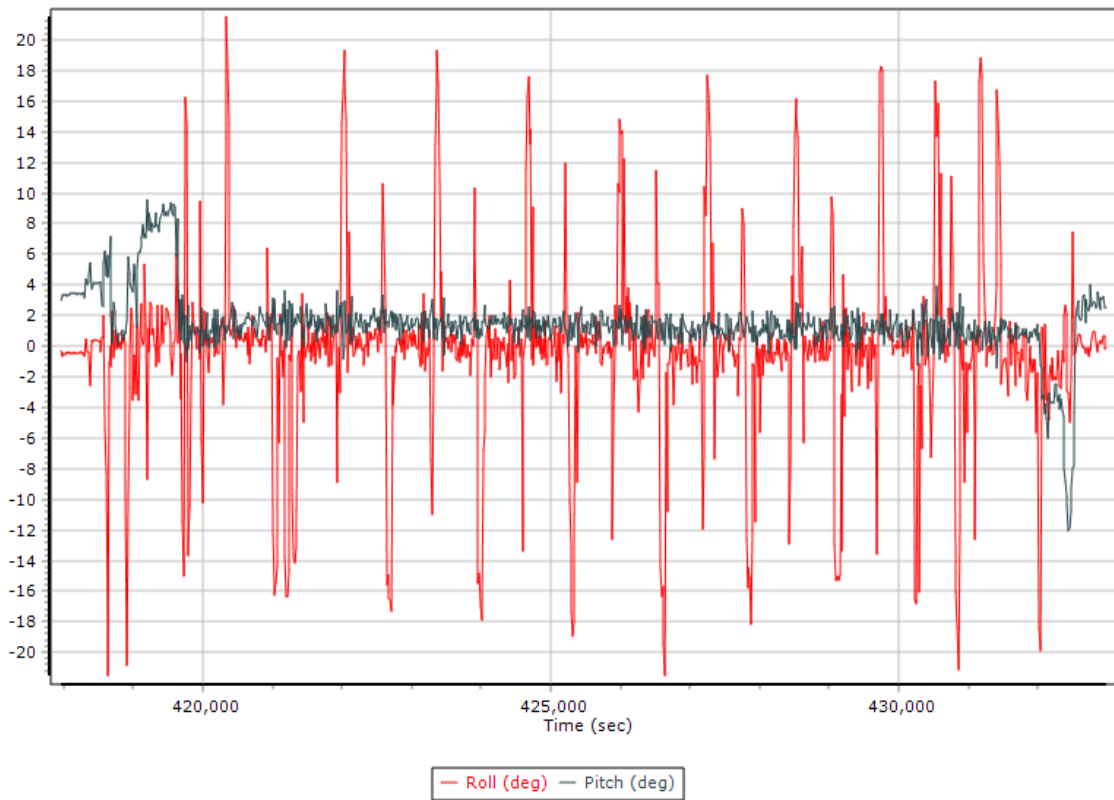
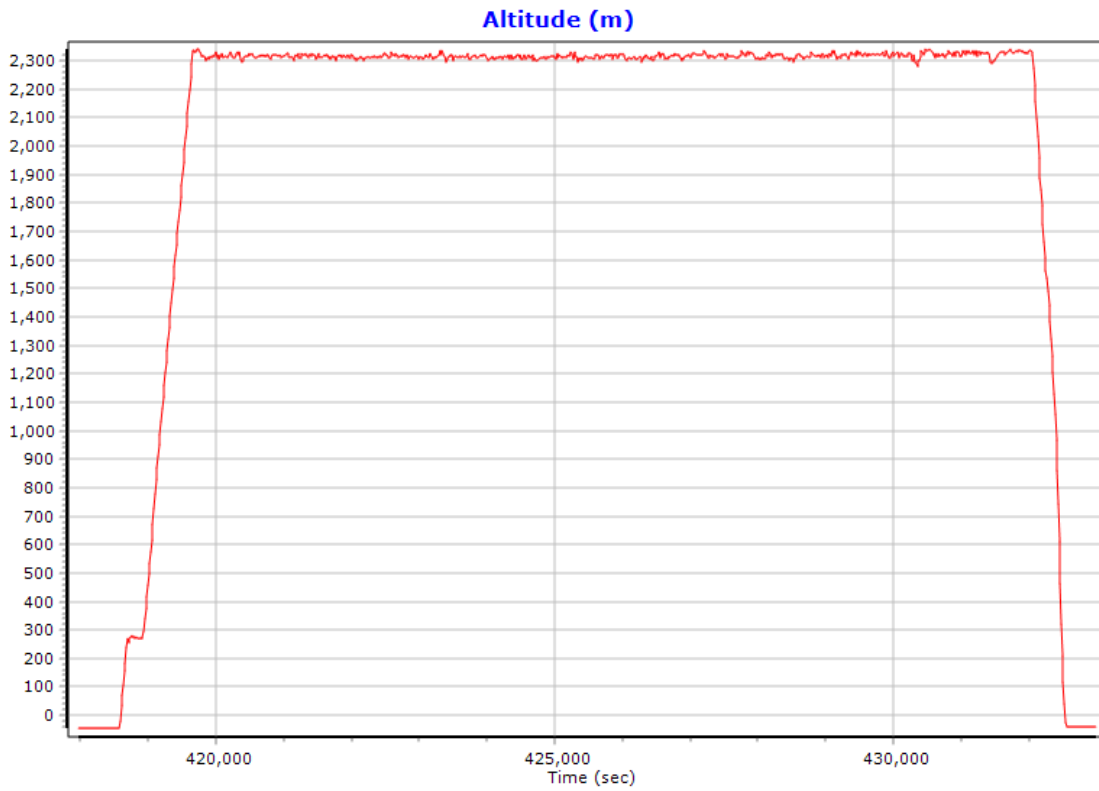


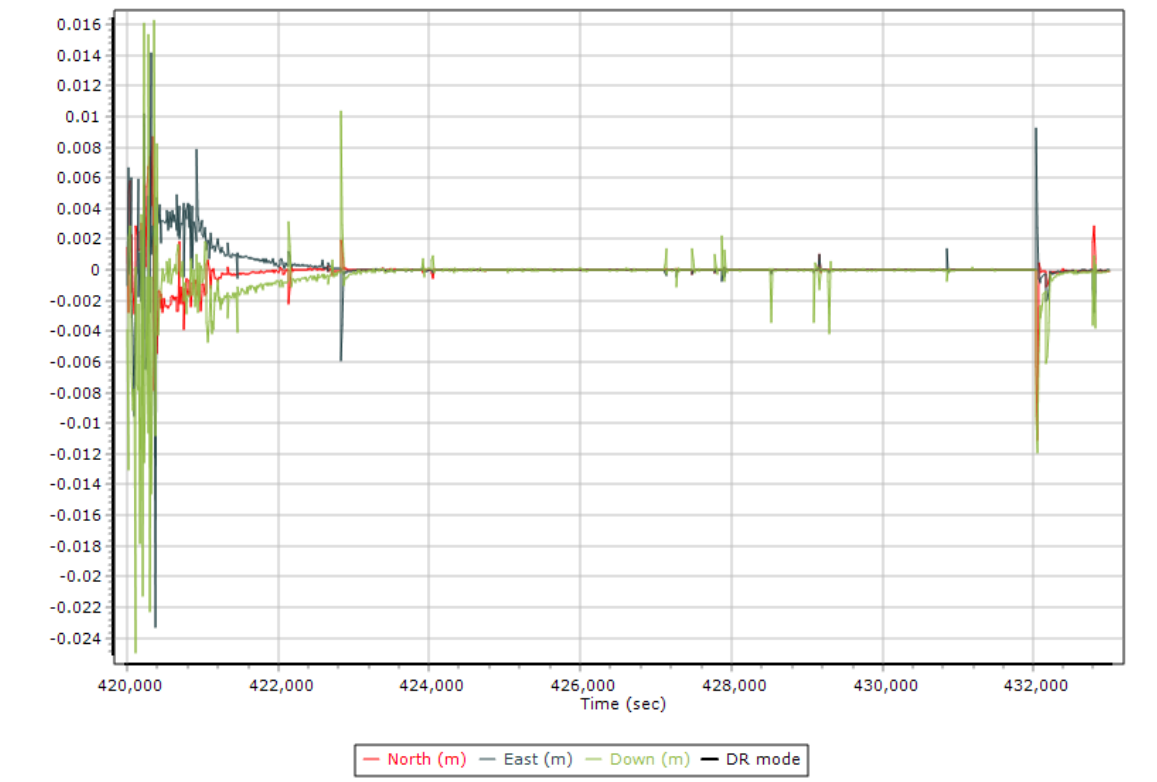
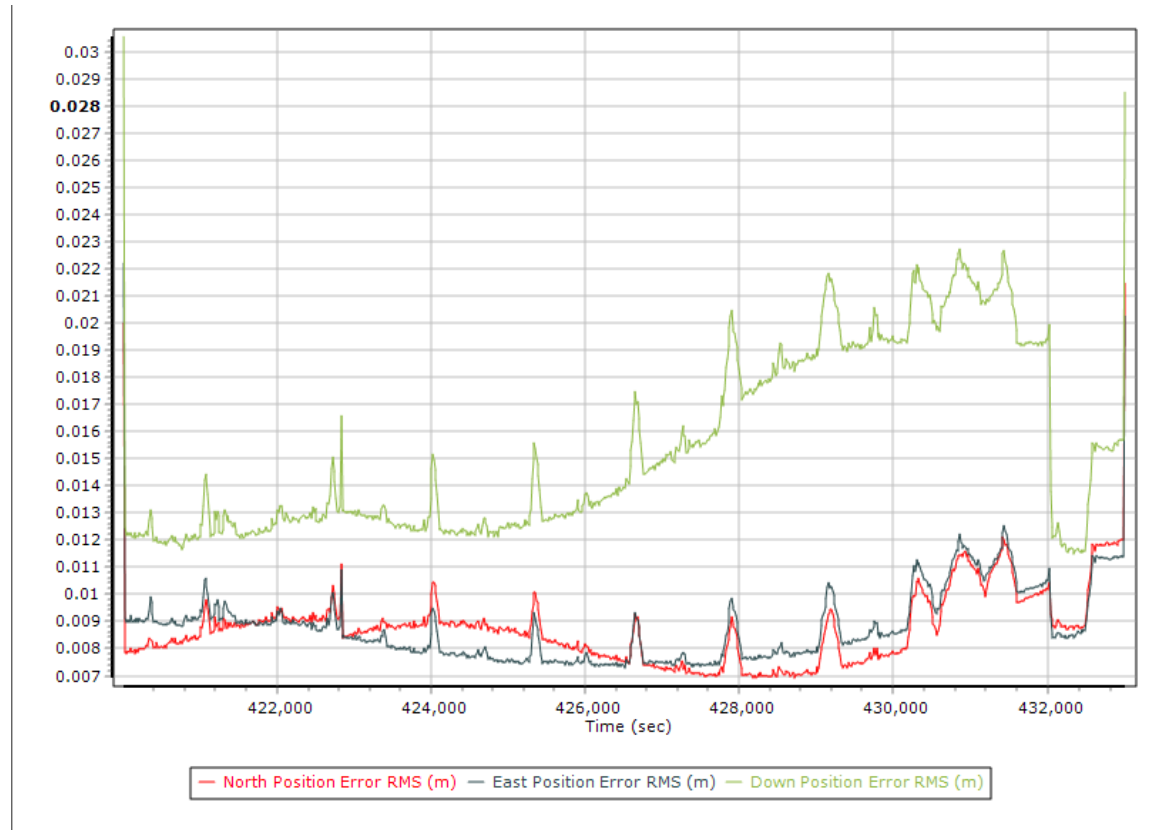


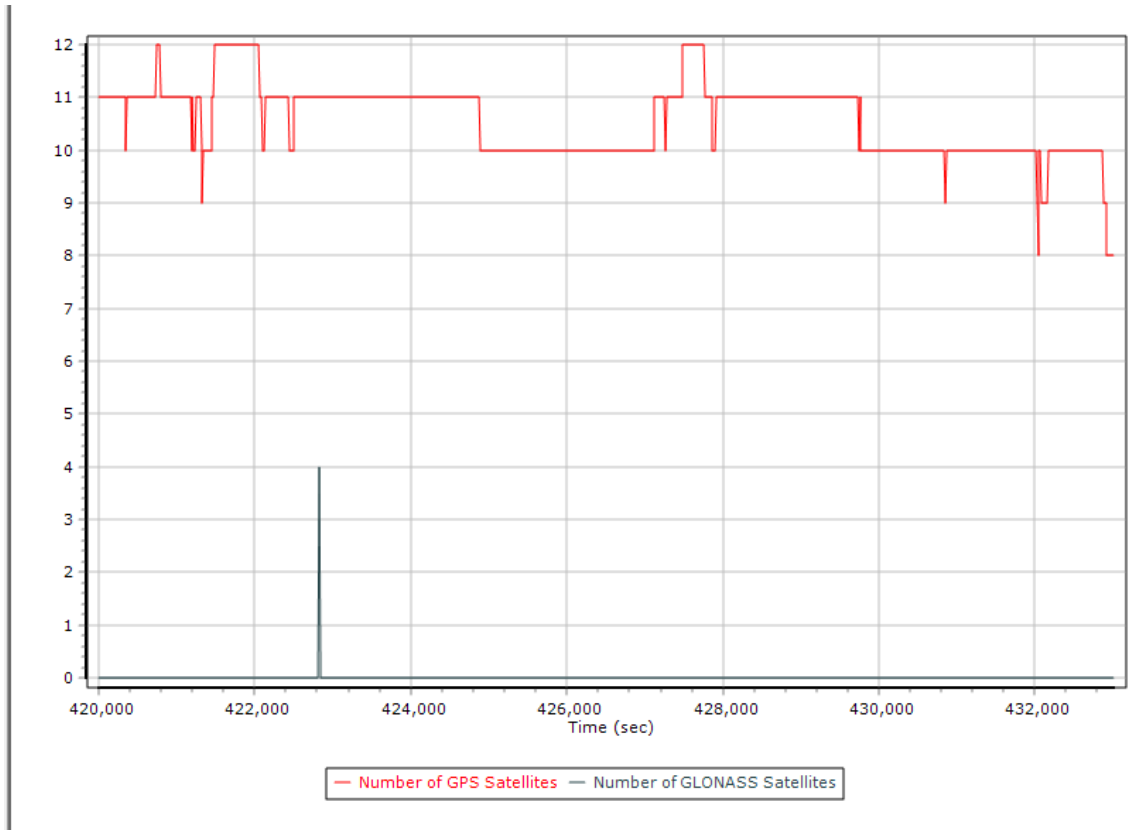
RBV19080B



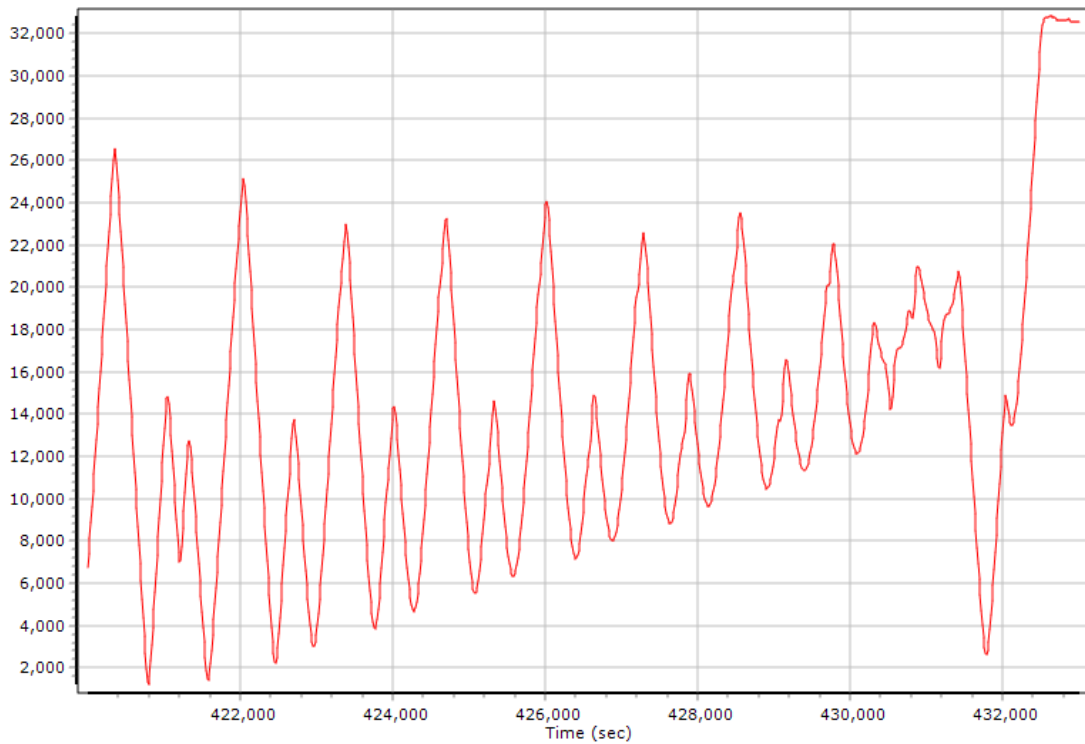


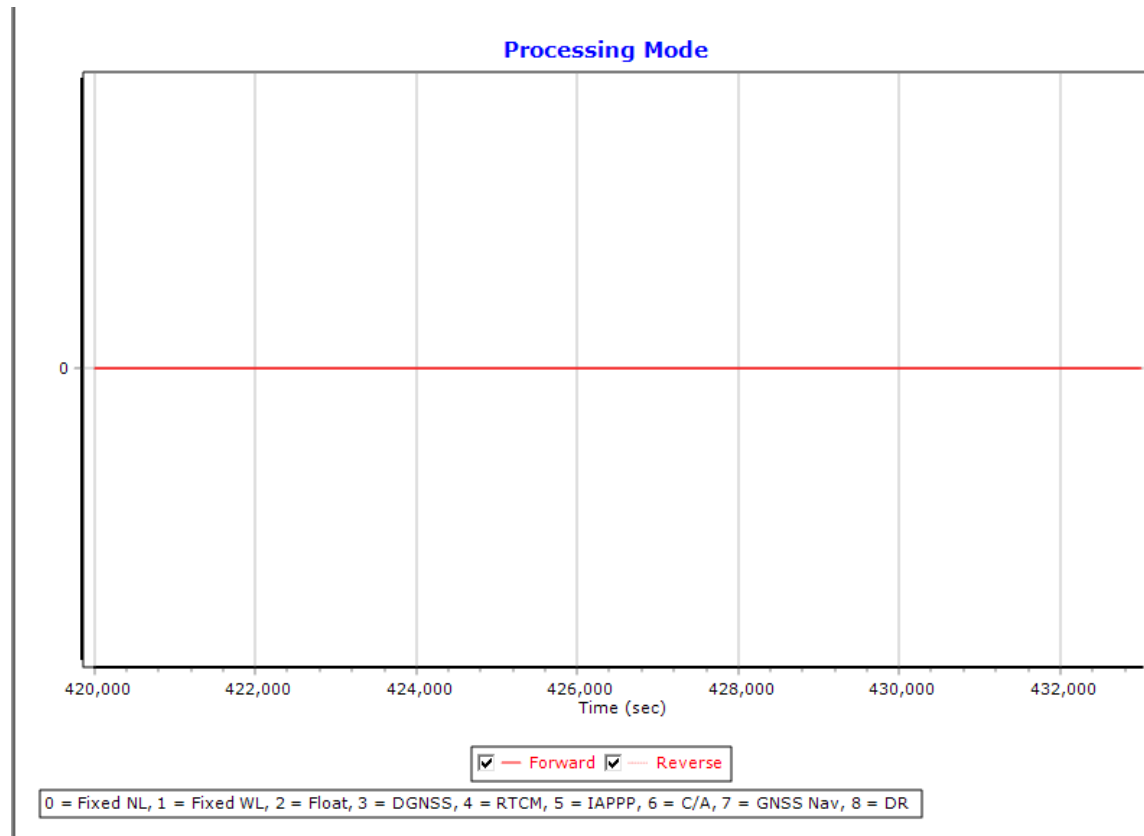
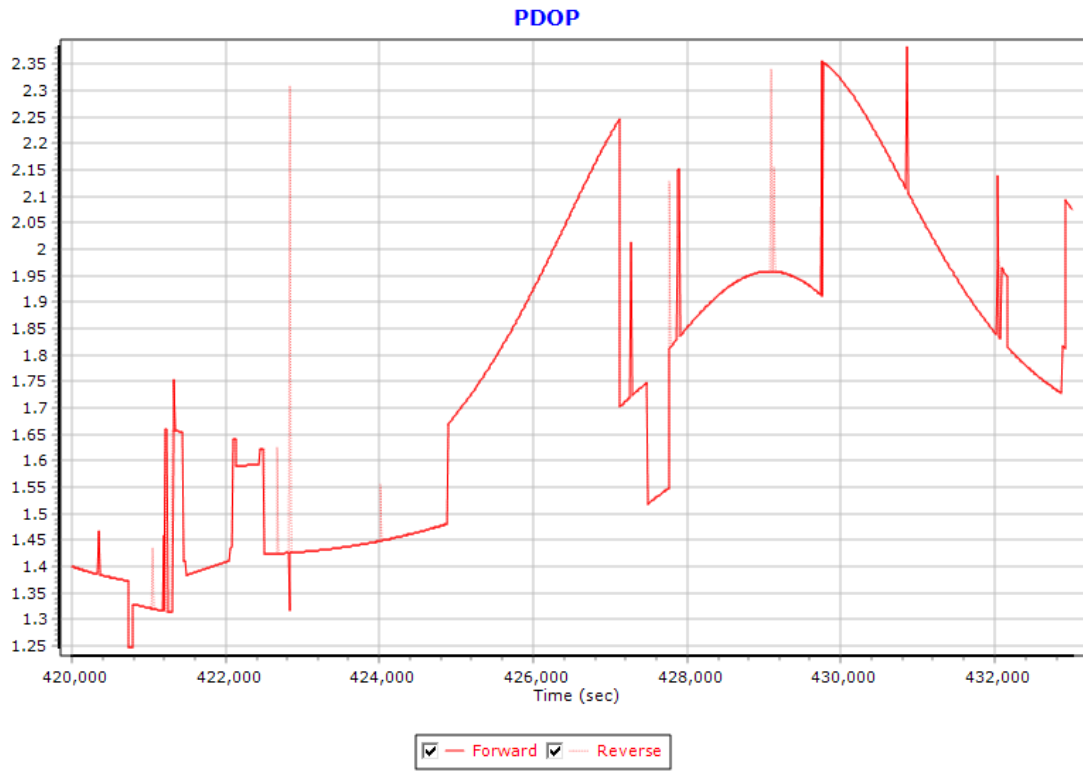




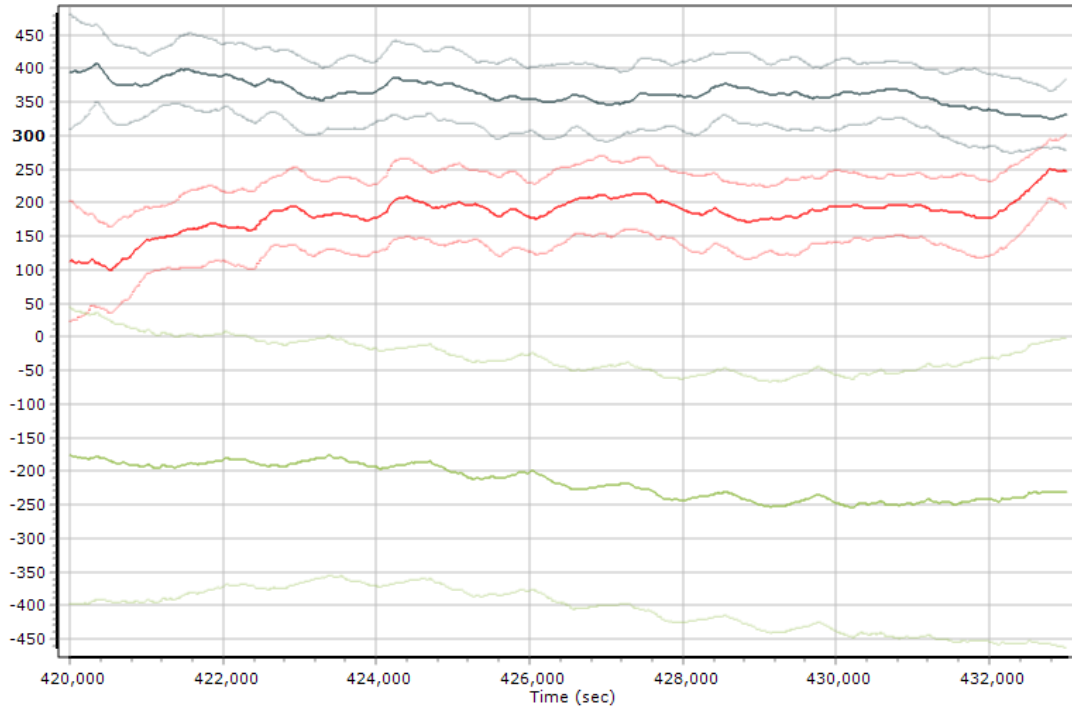


Baseline Length(m)

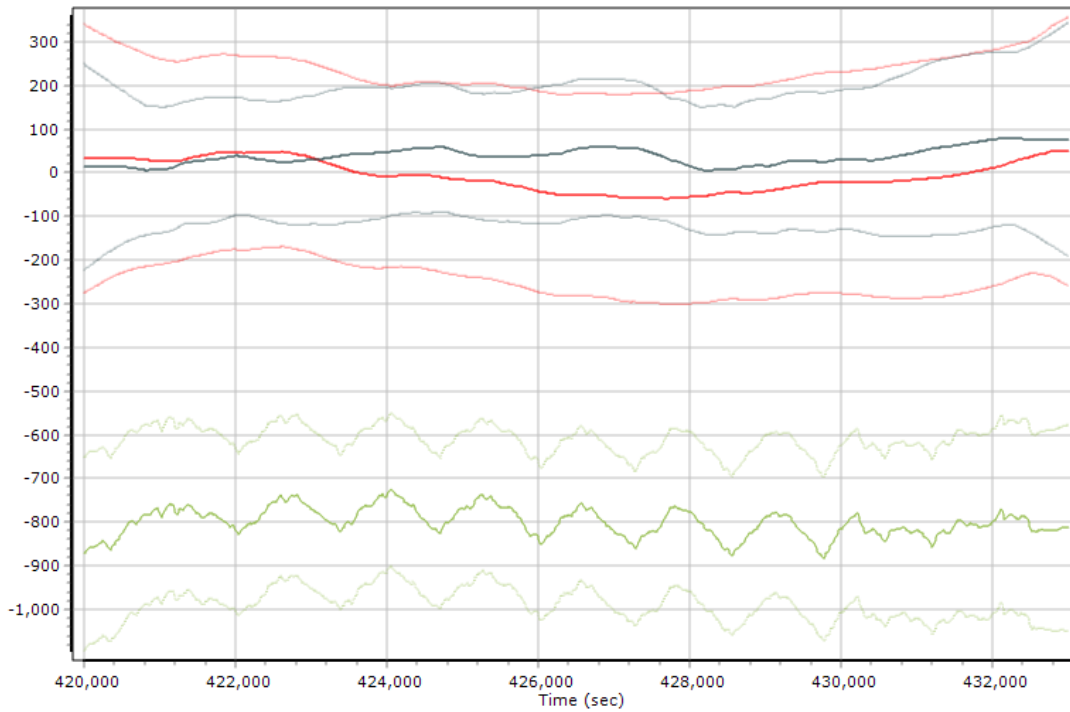




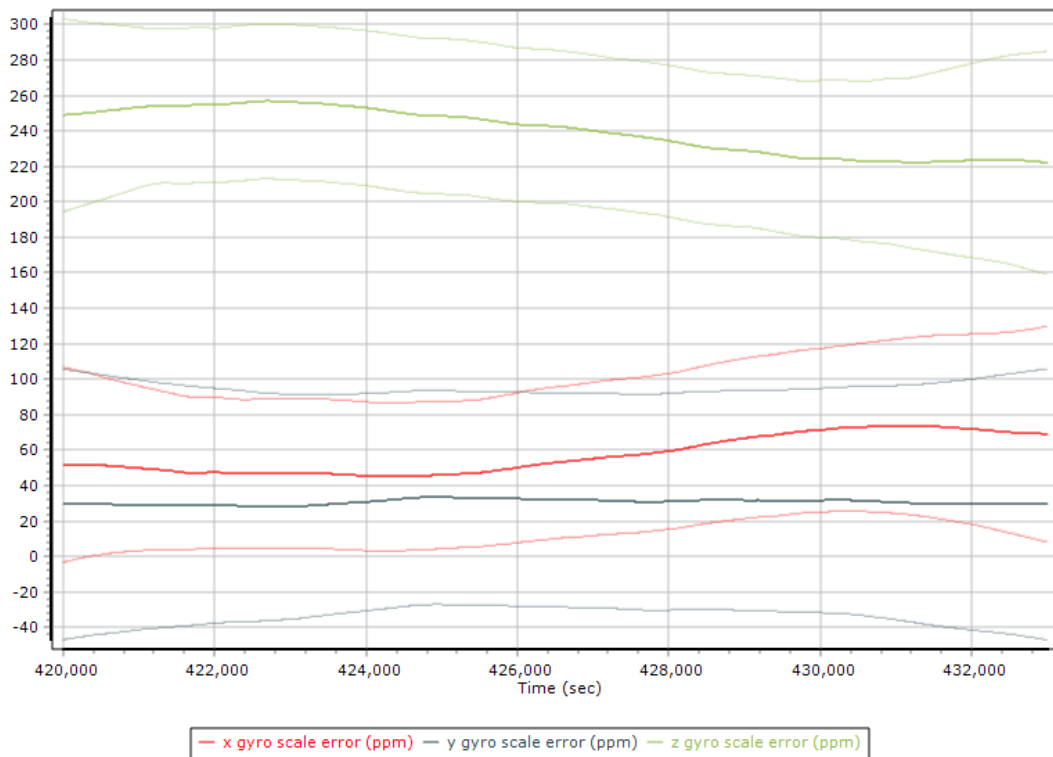
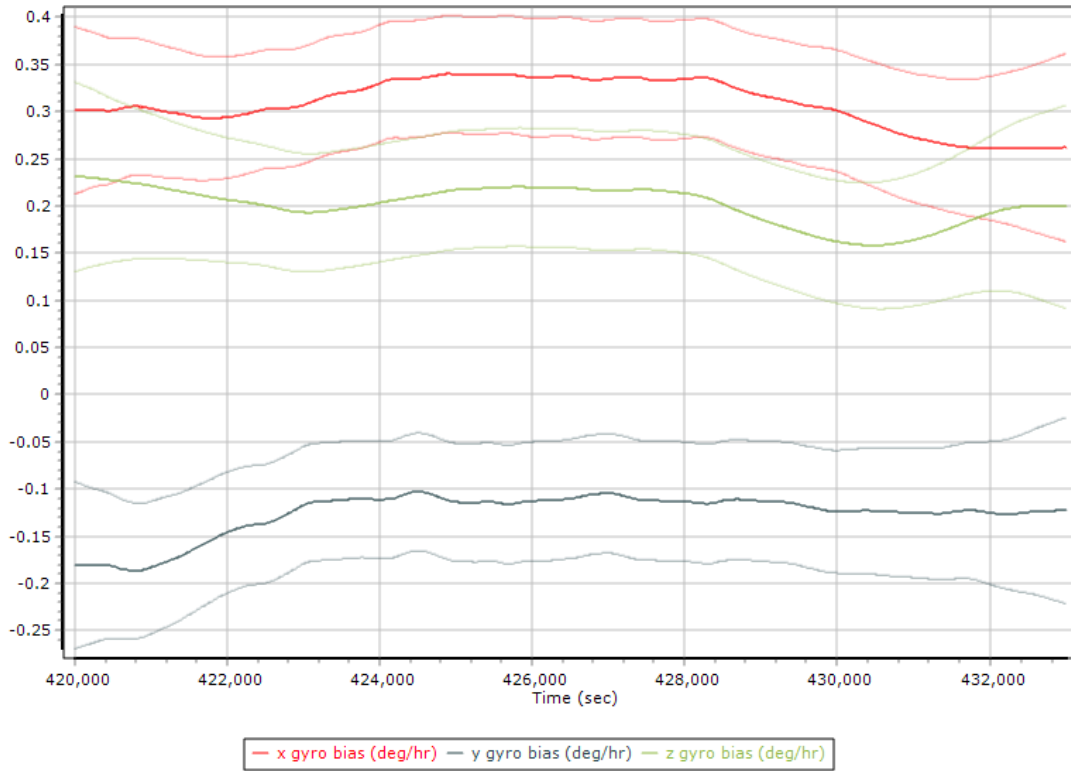
Sensor Errors



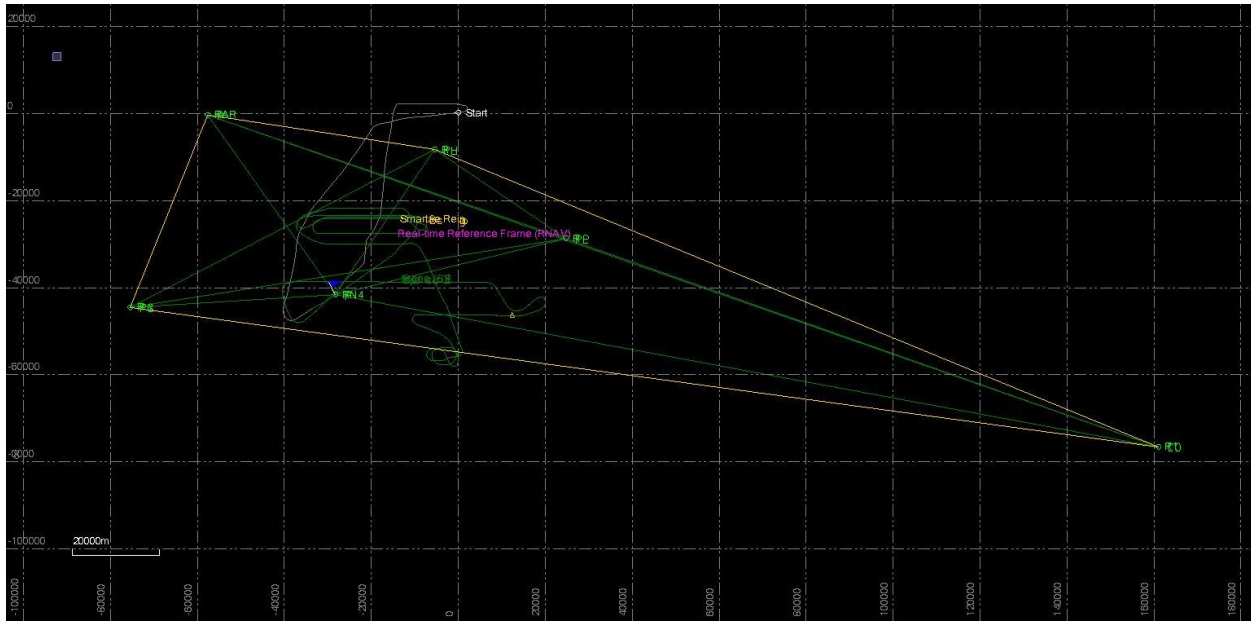
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



RBV19082A



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: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 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: 559680.359

End: 566971.570

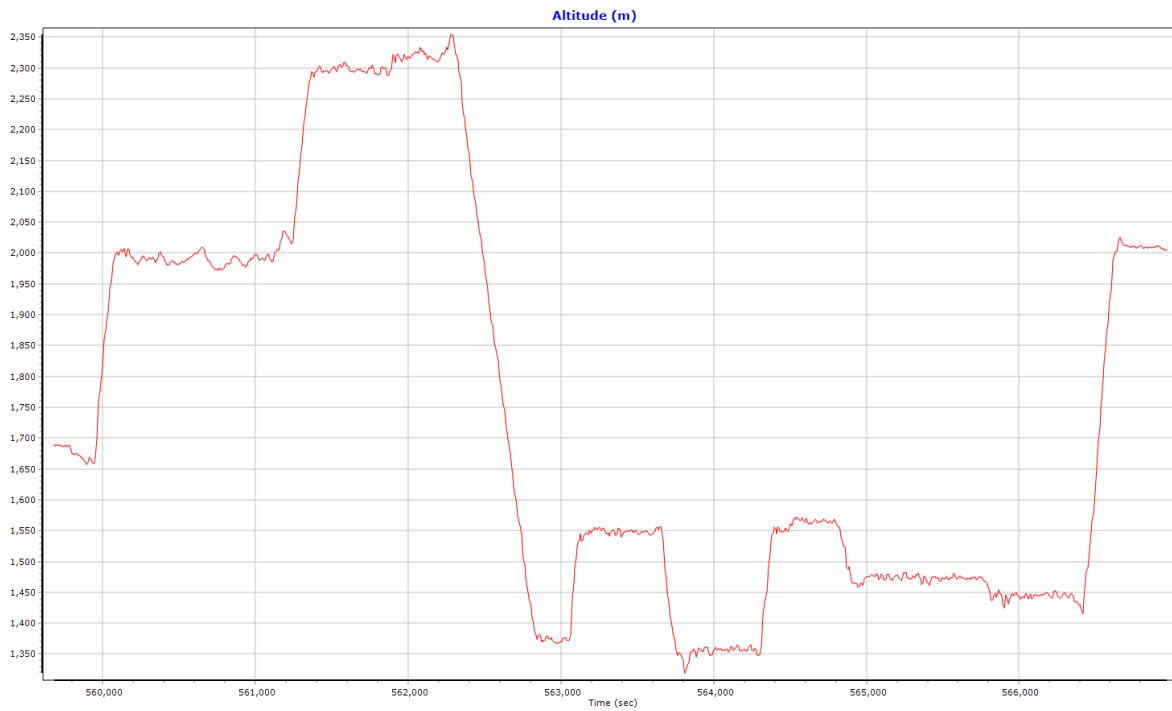
Entire time interval

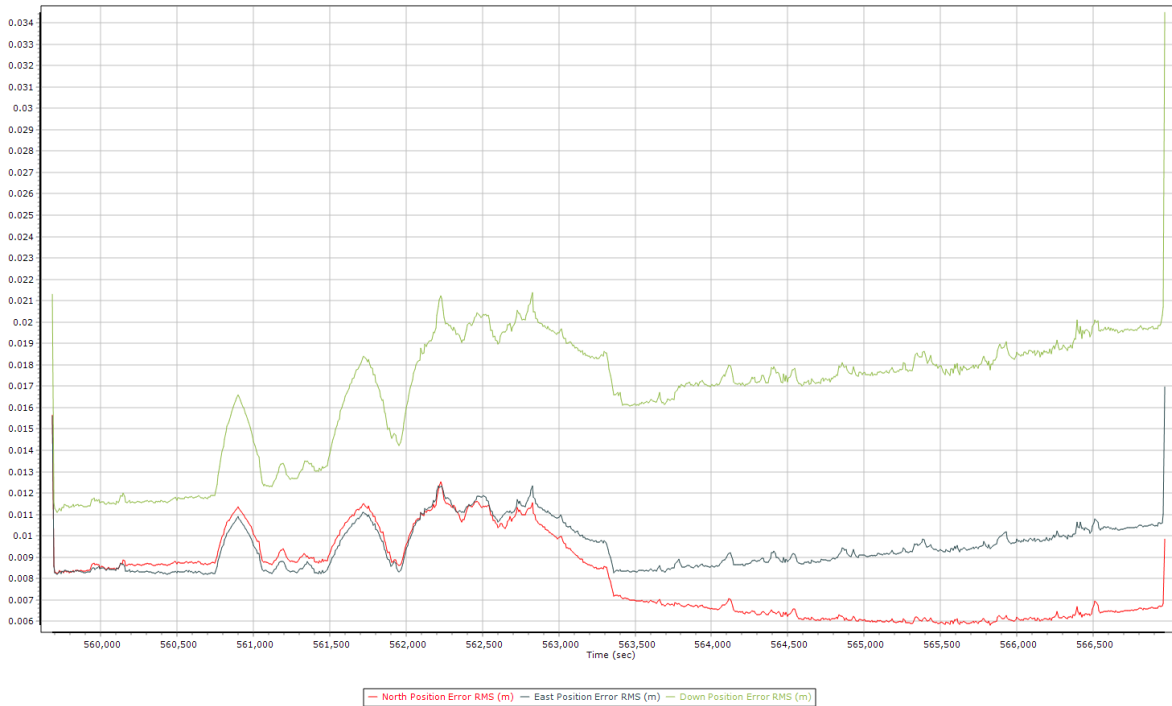
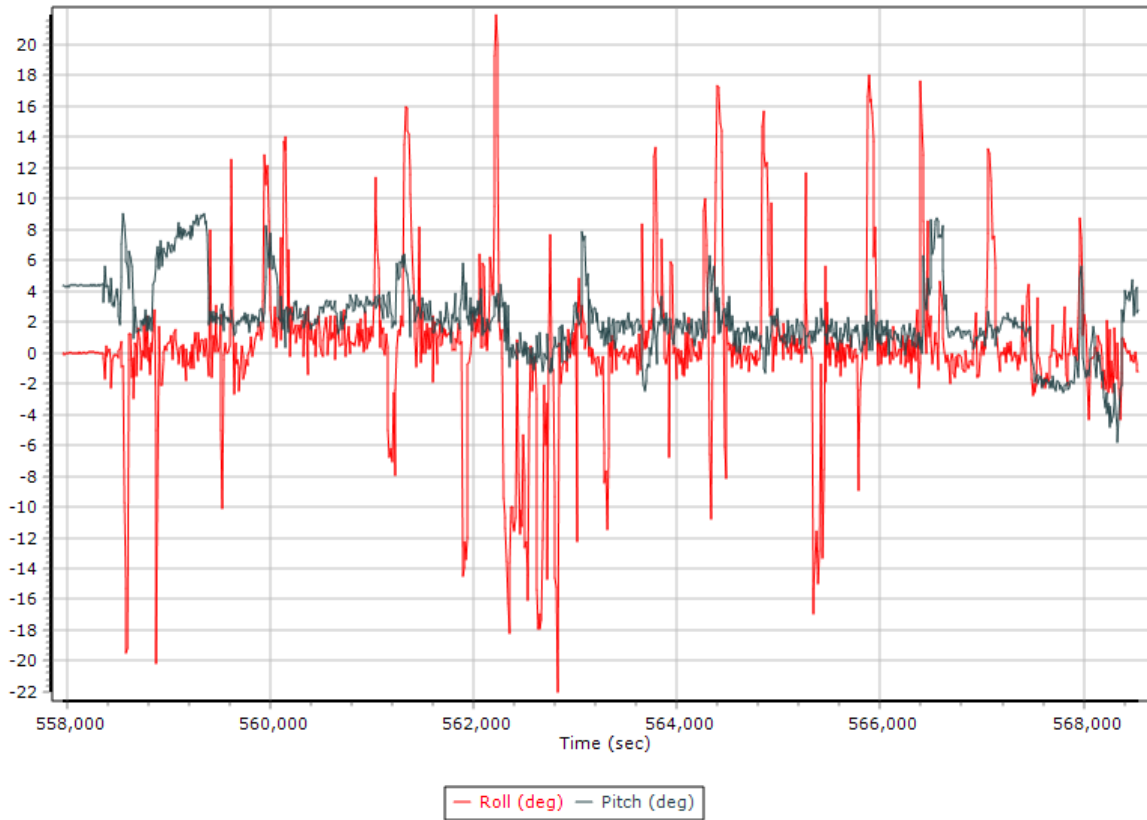
Seconds of start week

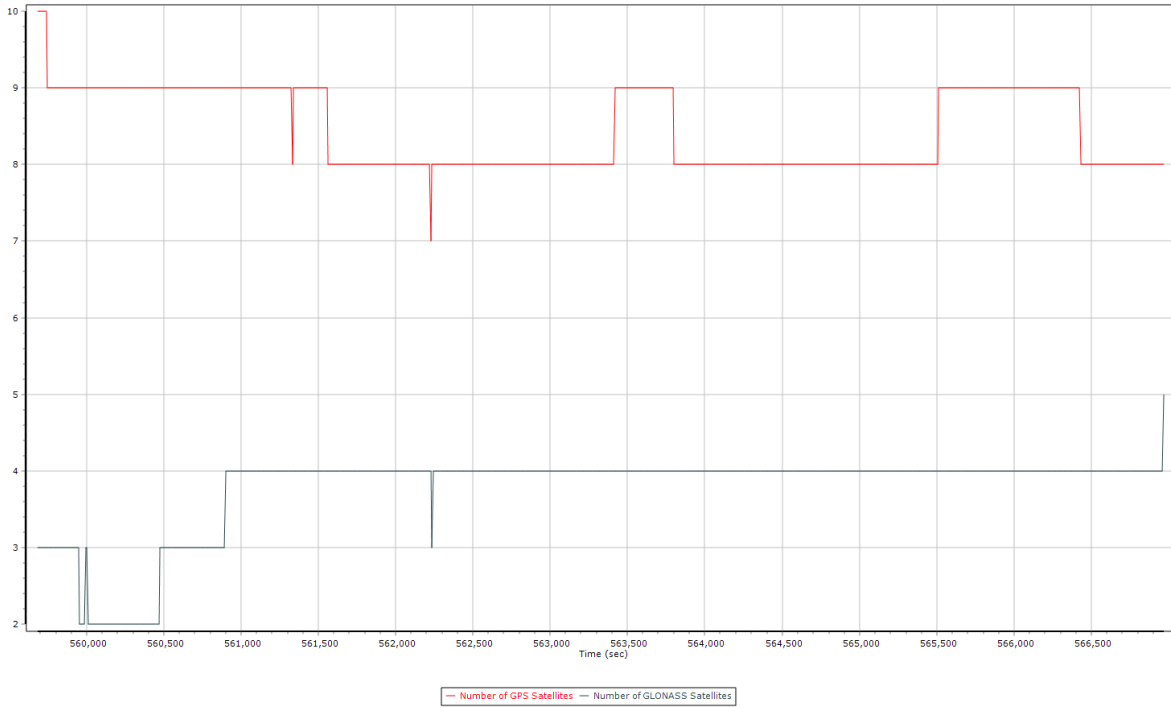
UTC Offset: 18.000

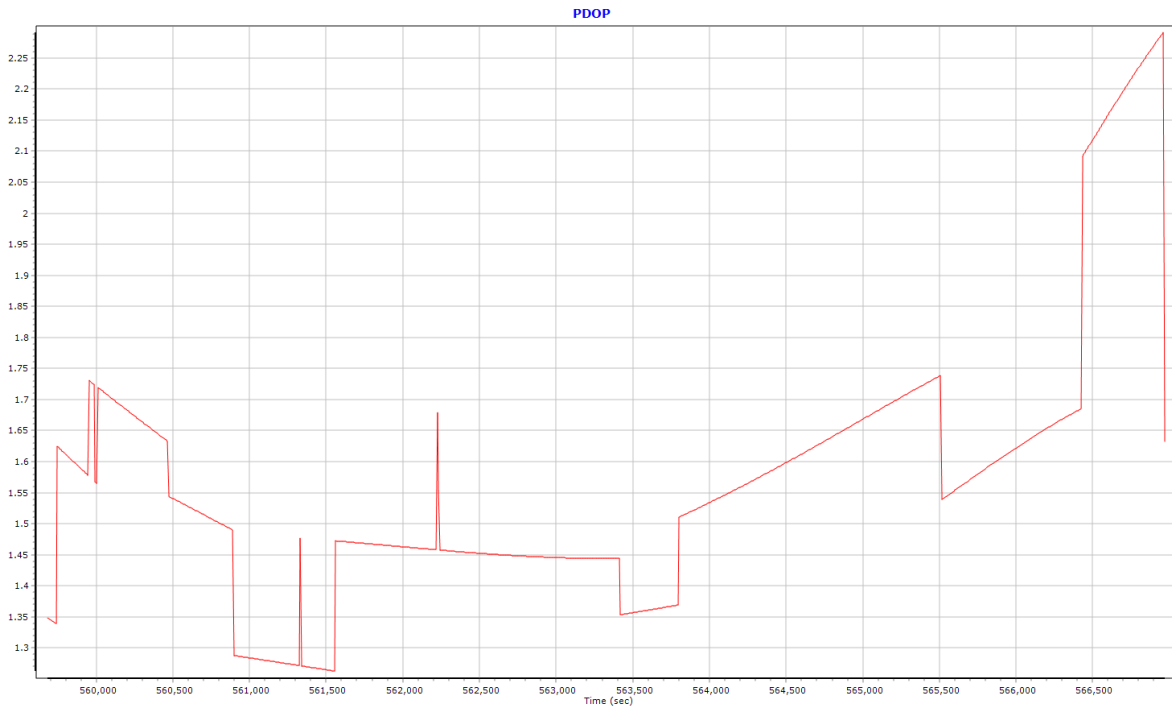
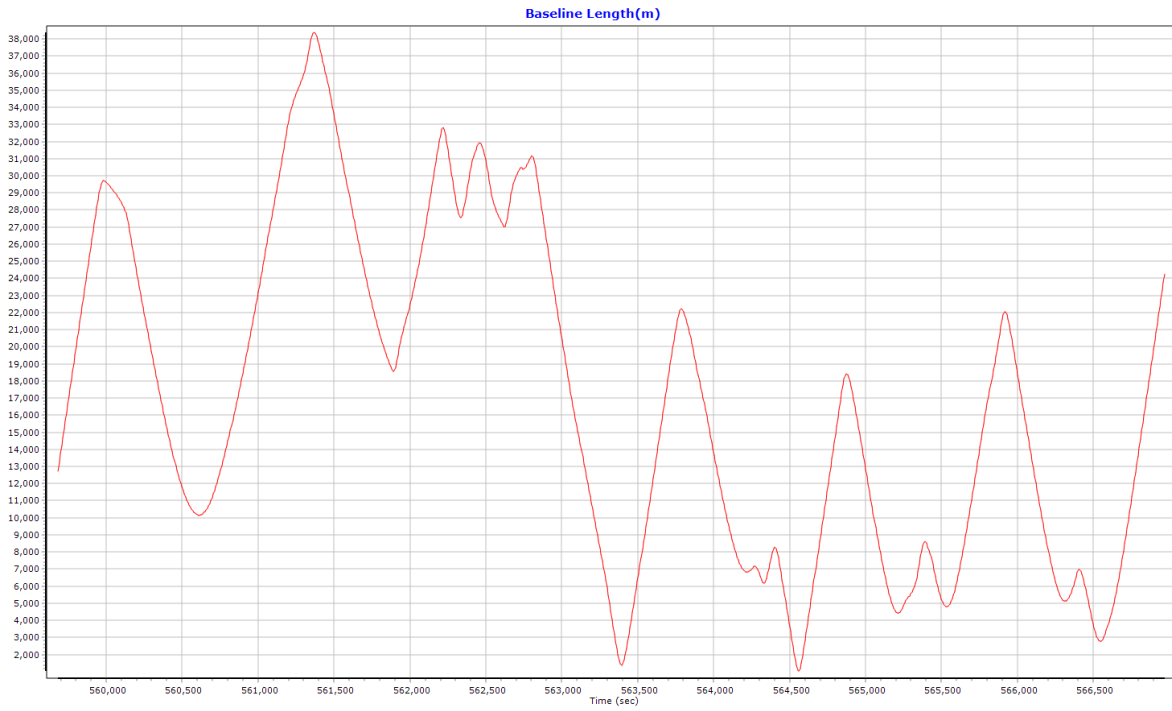
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

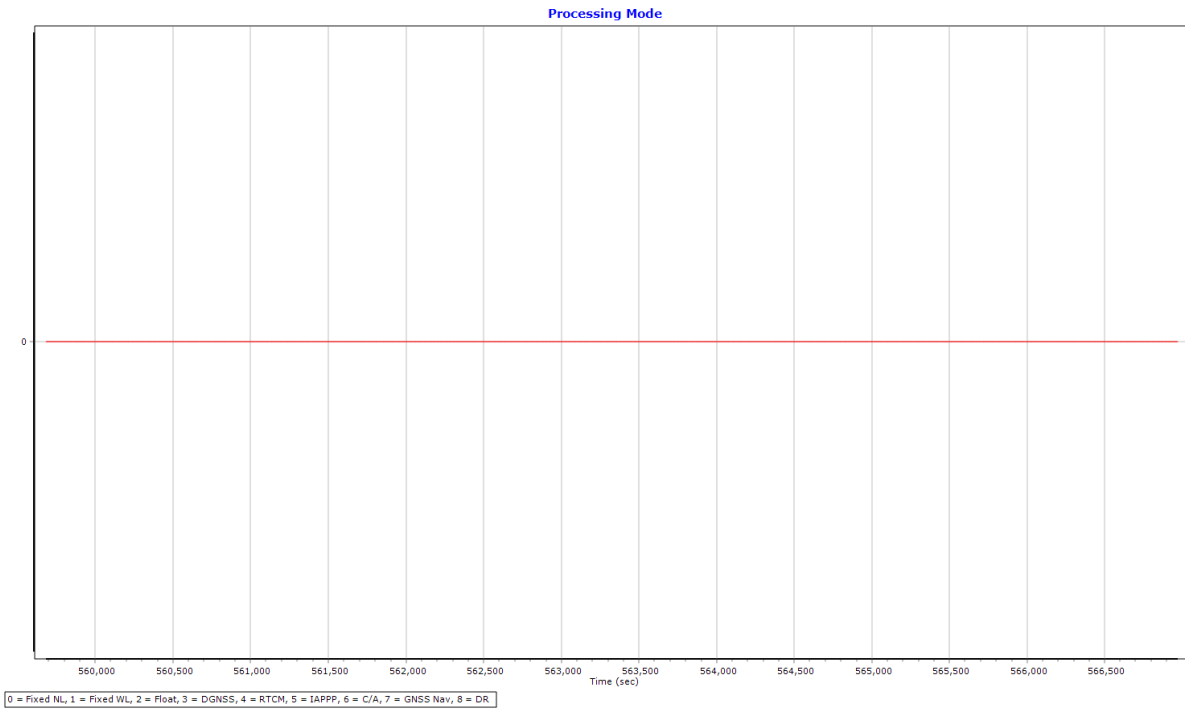
OK Cancel



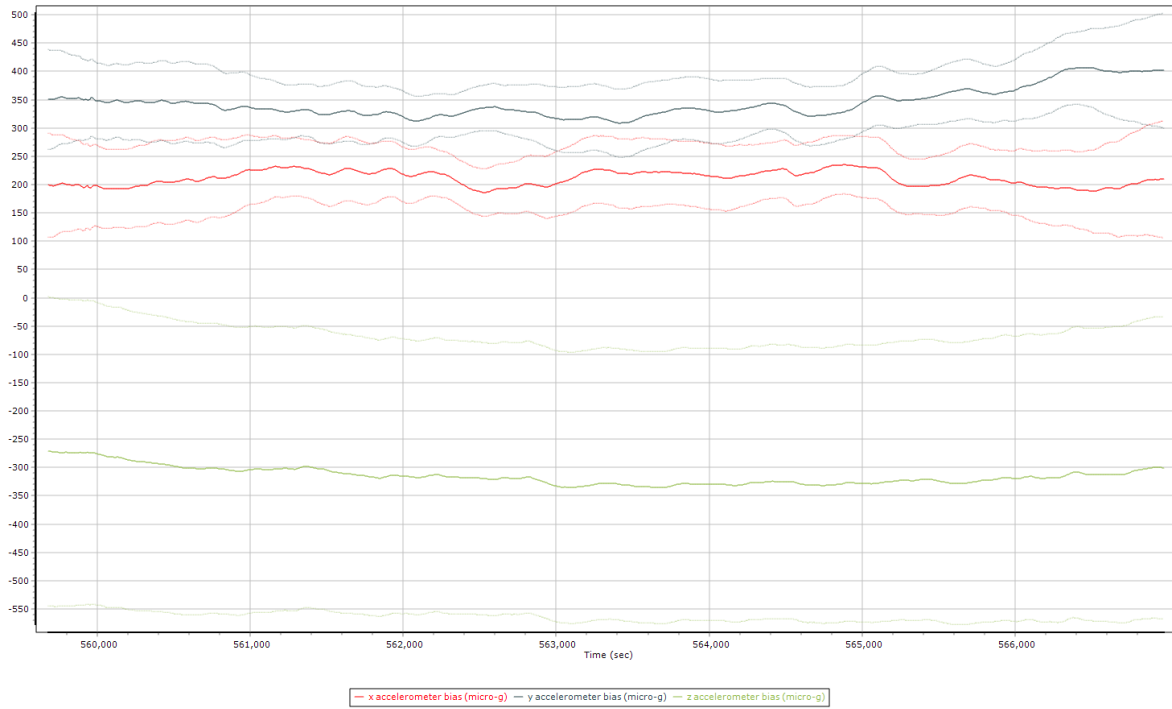


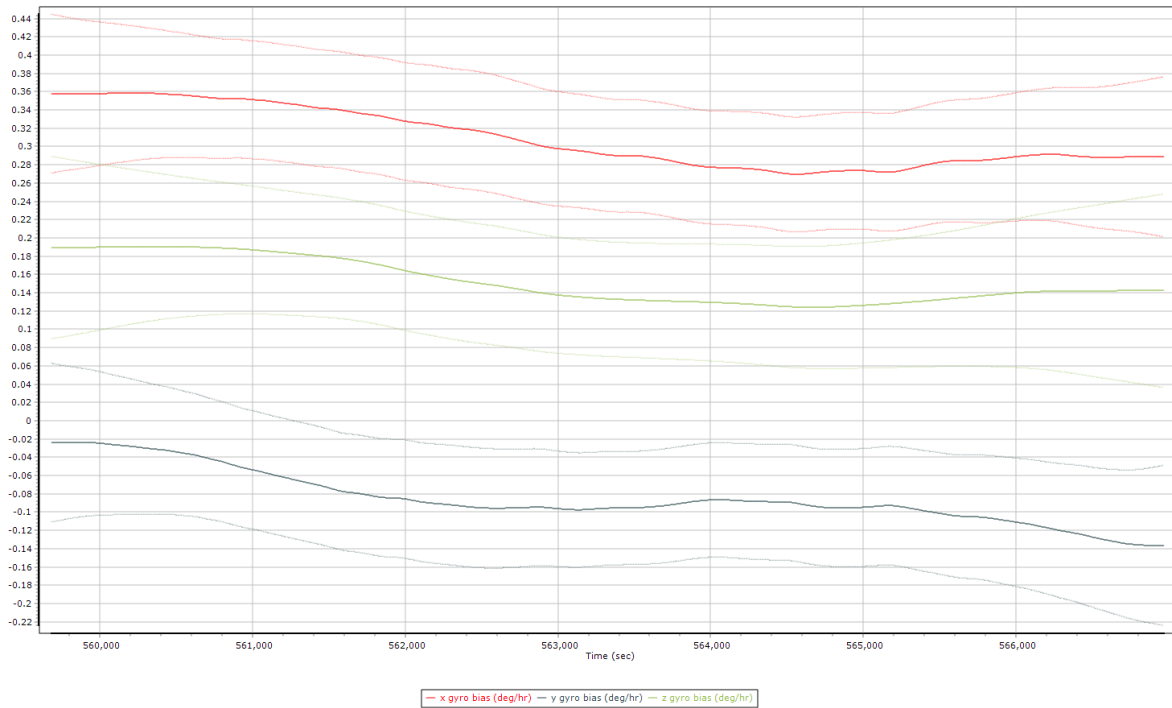
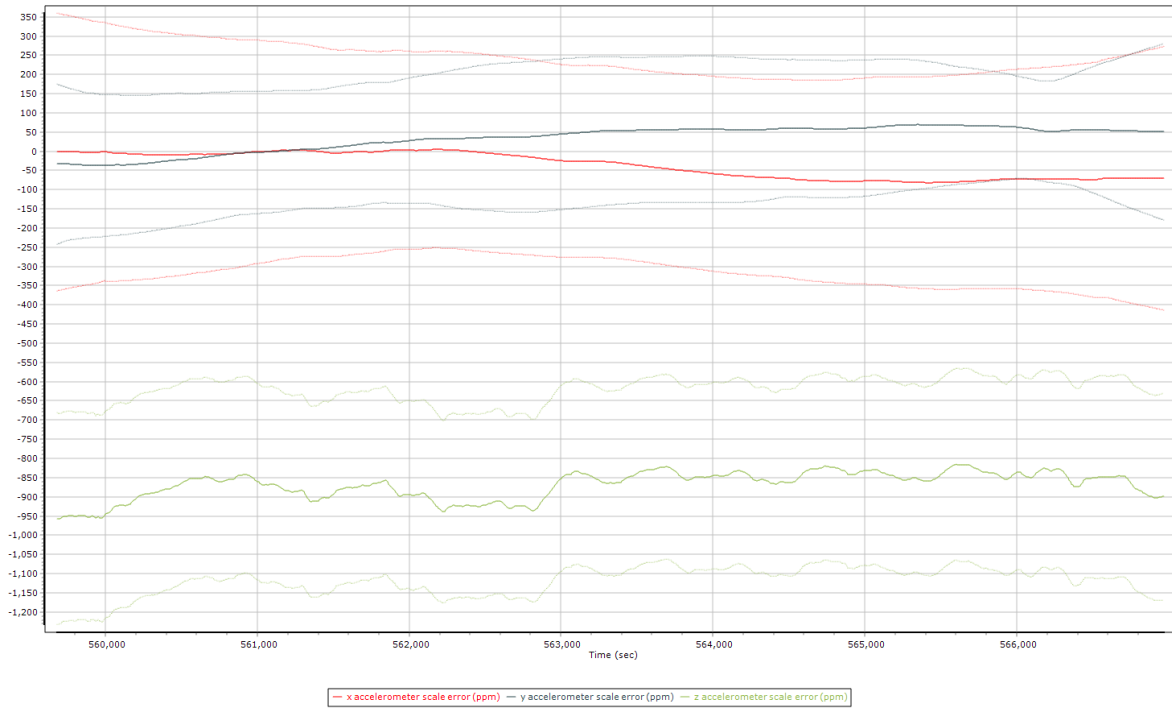


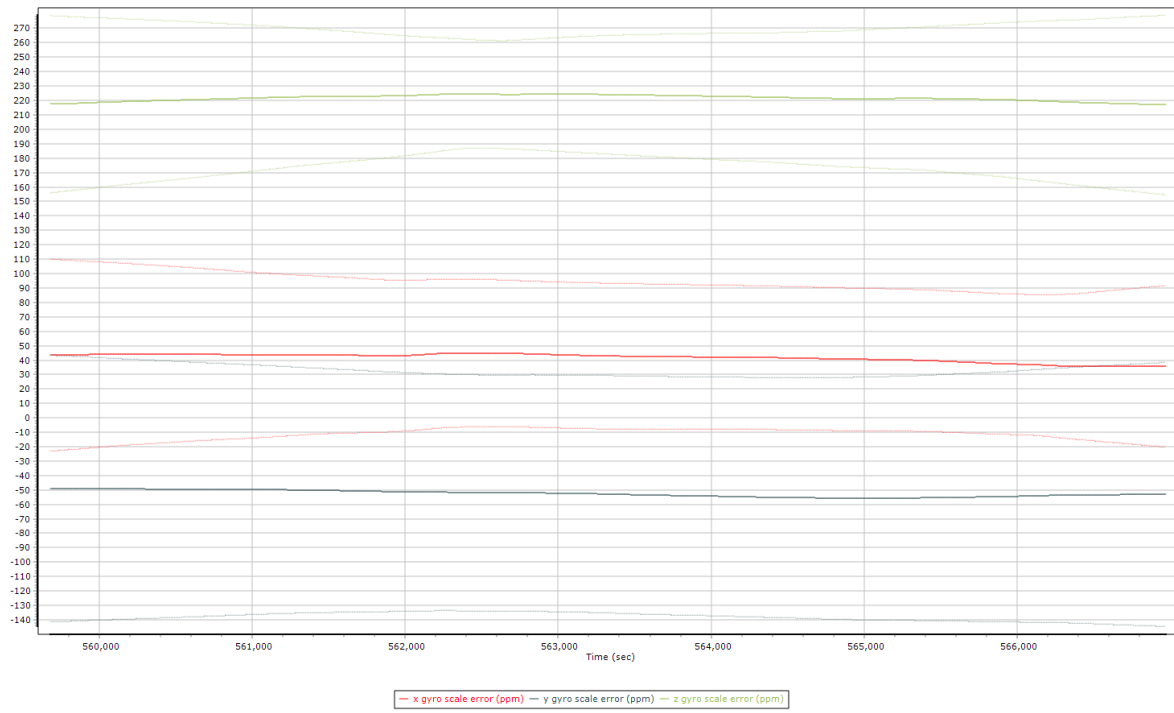




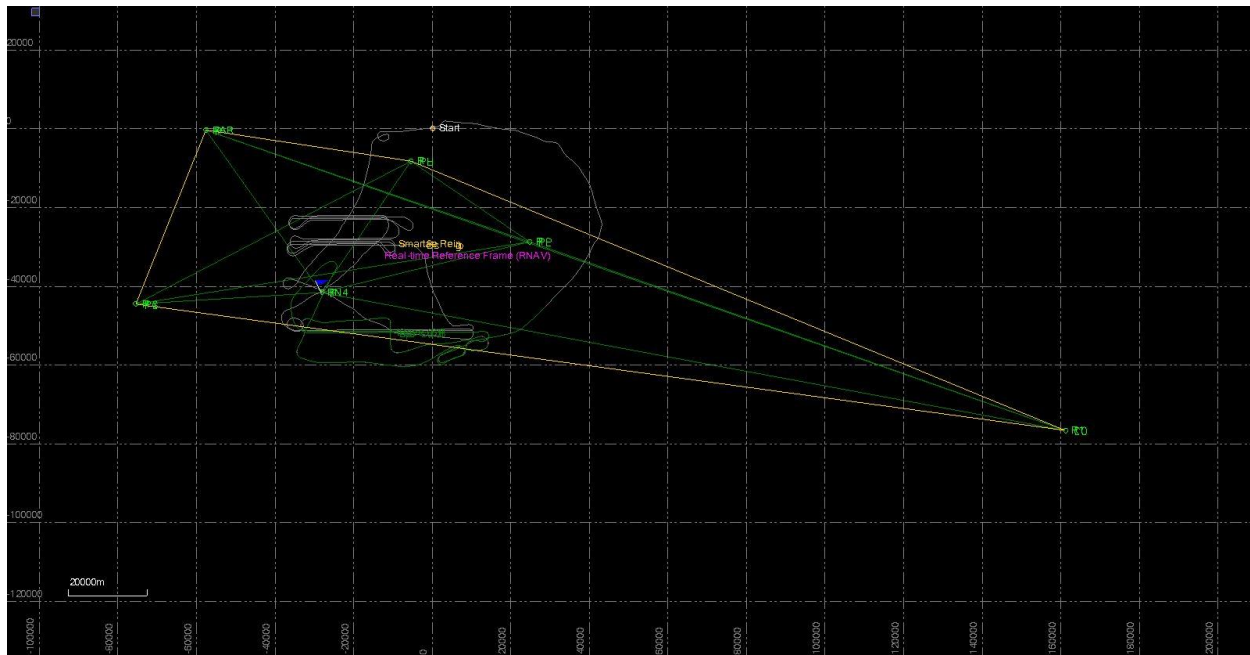
Sensor Errors

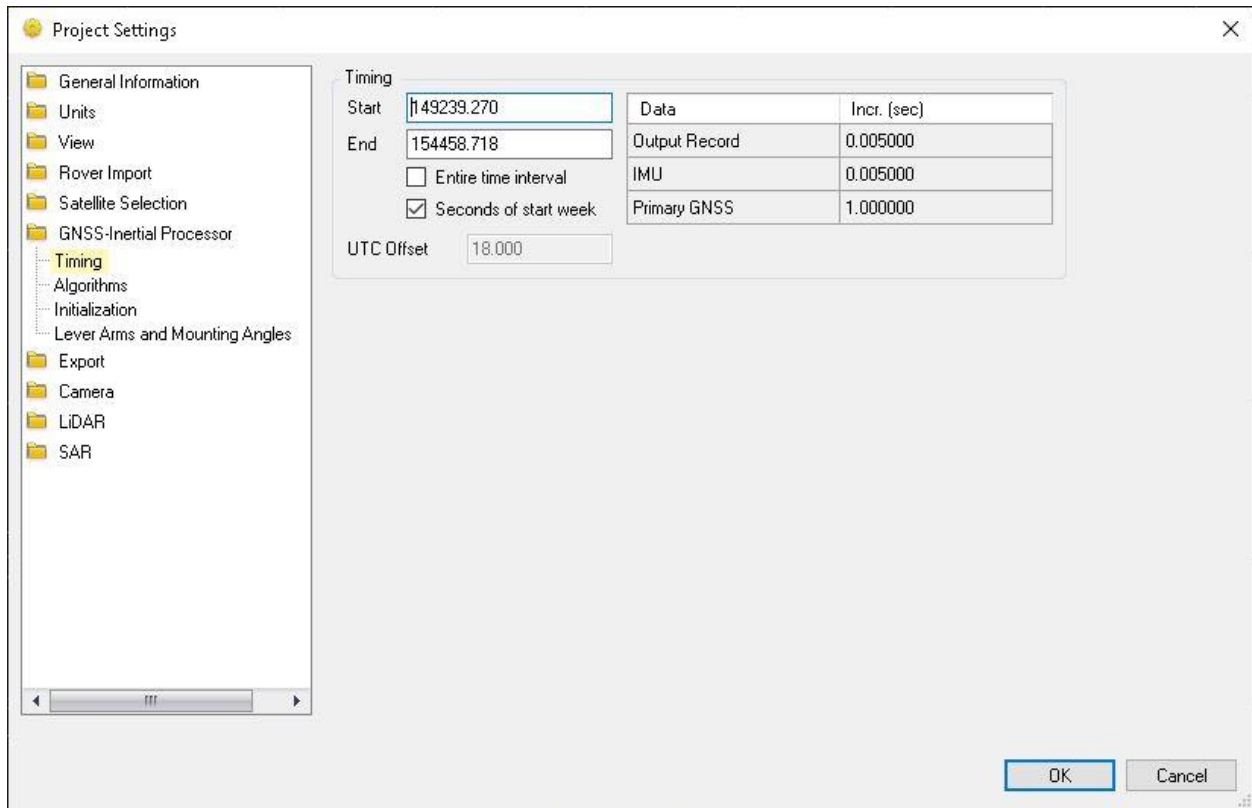
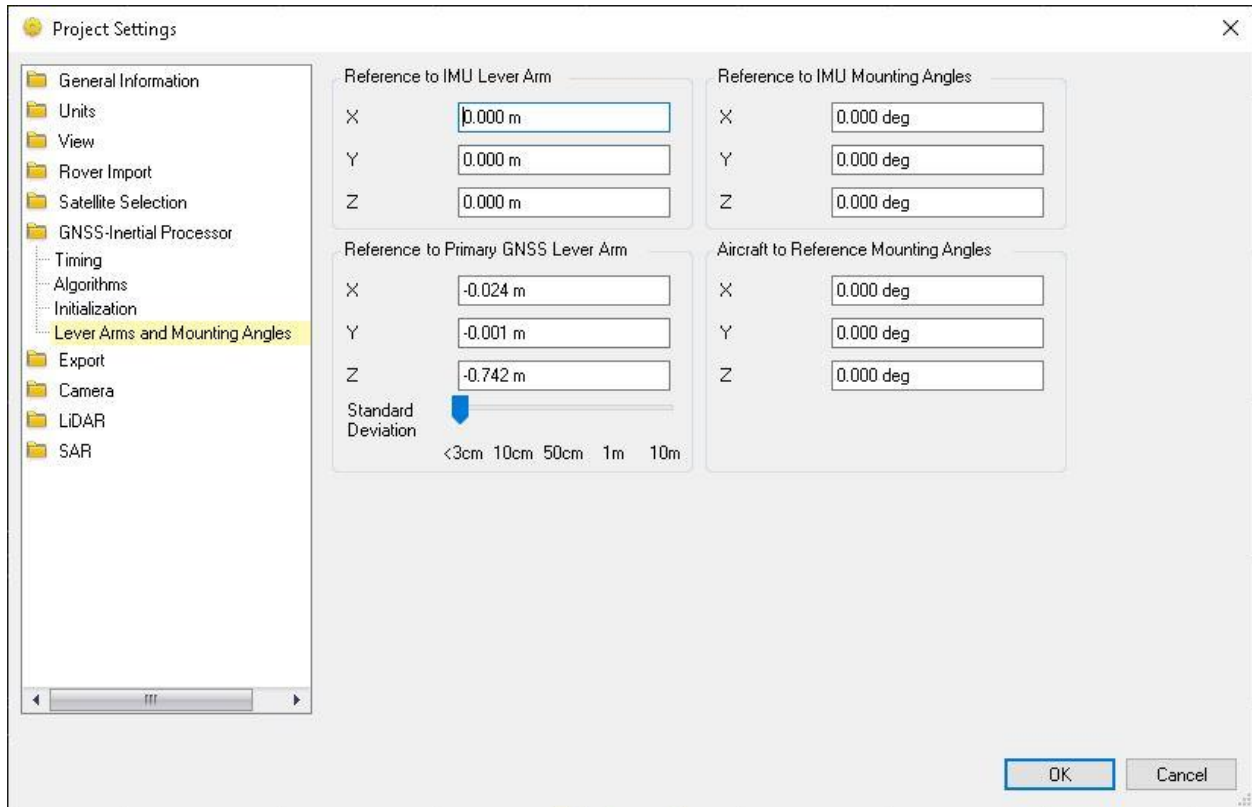


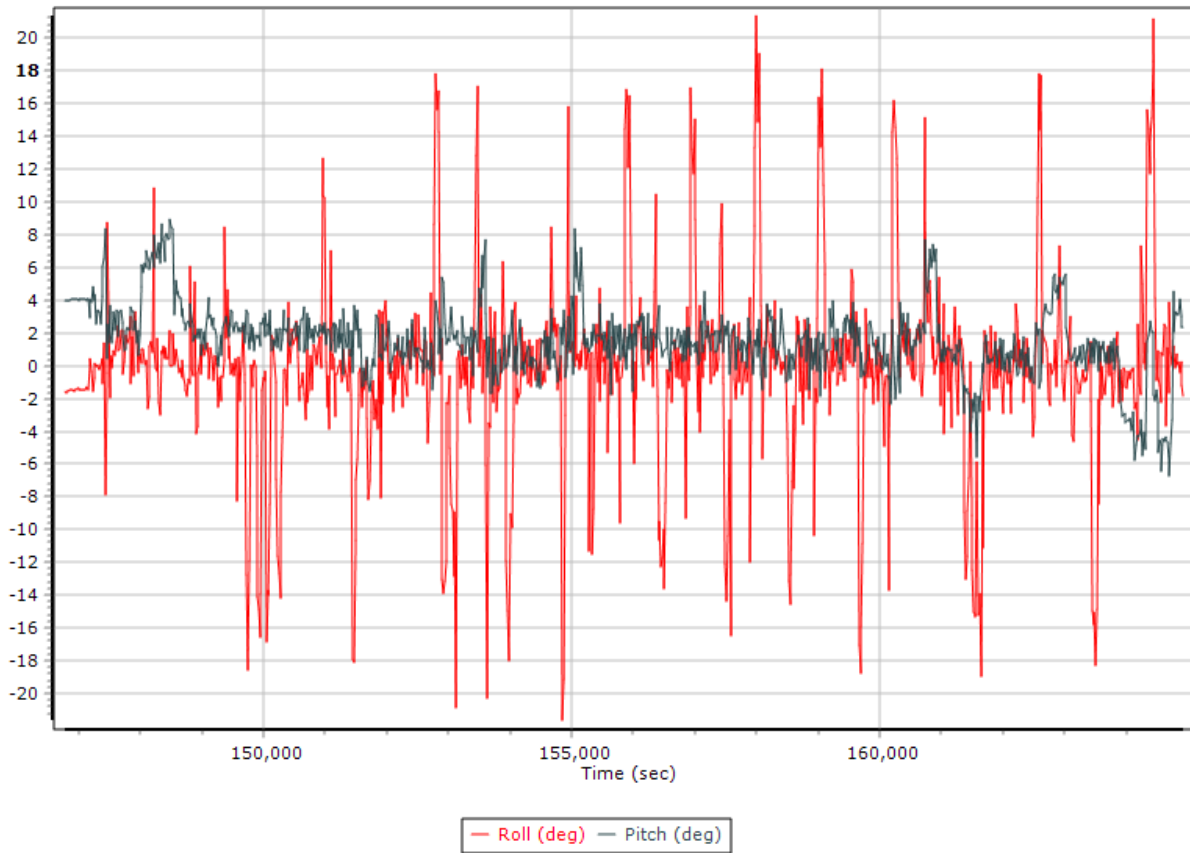
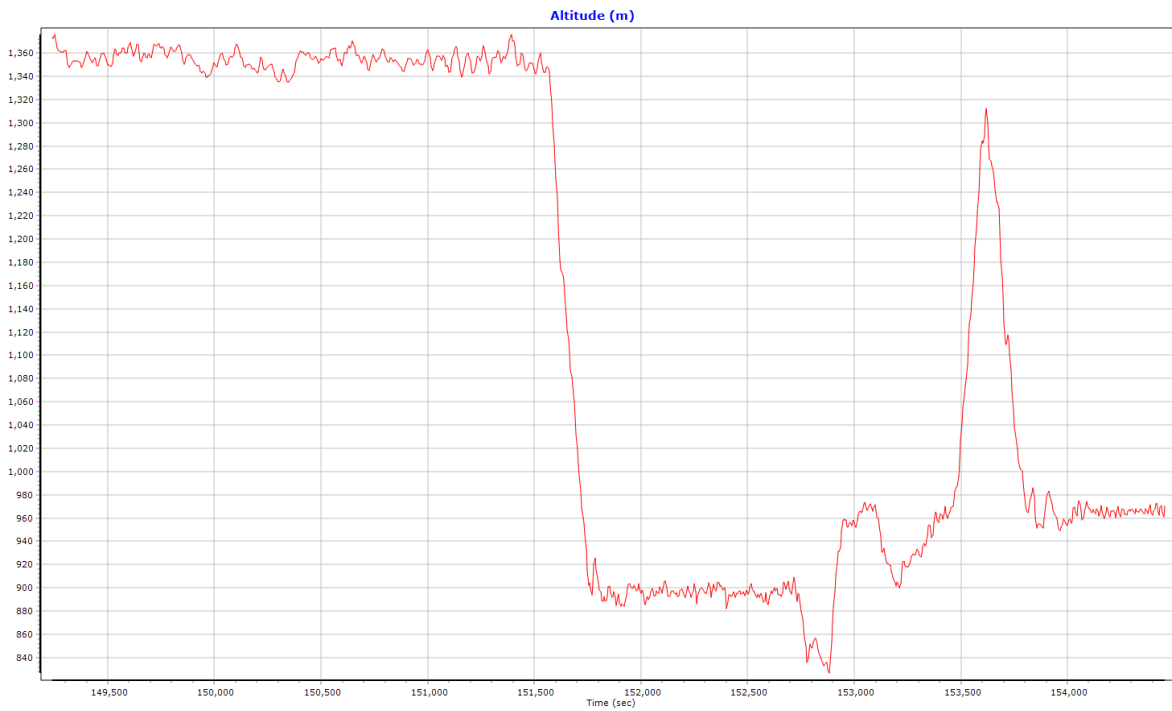


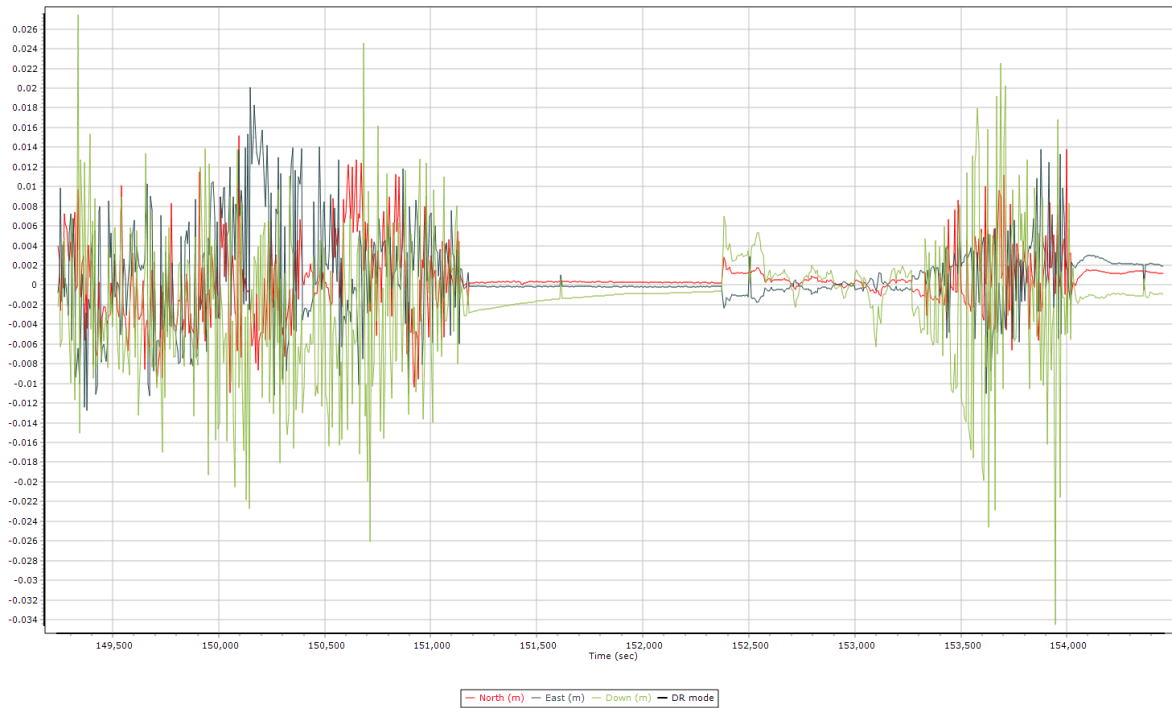
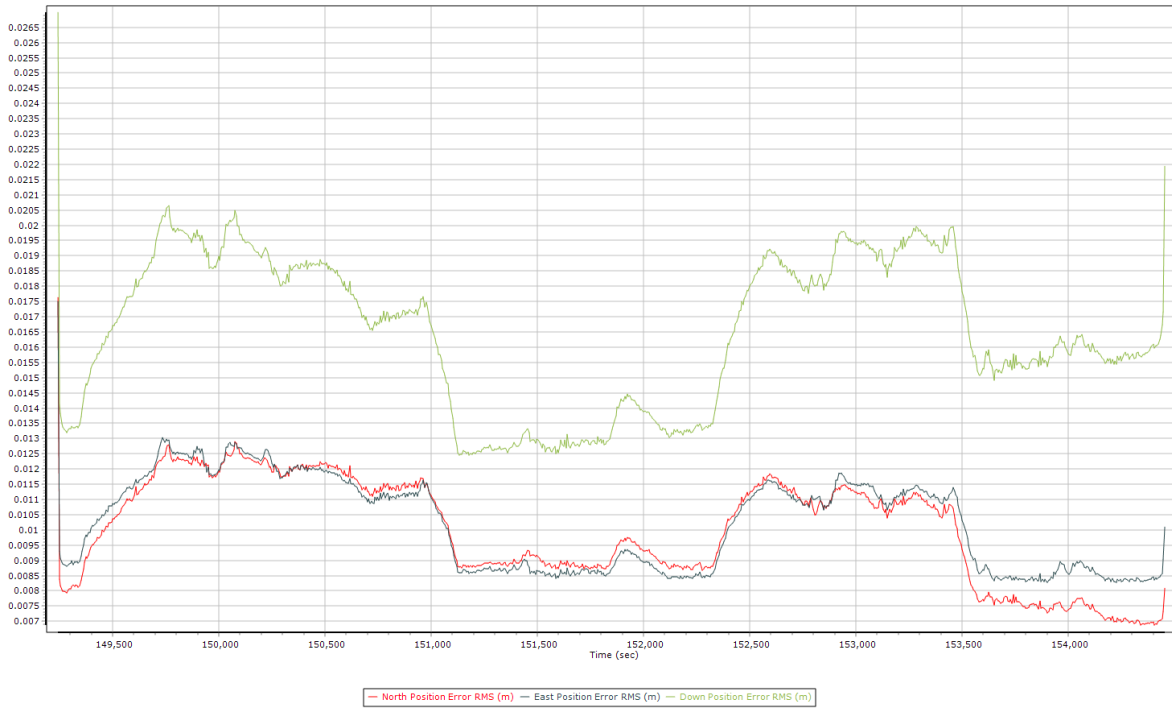


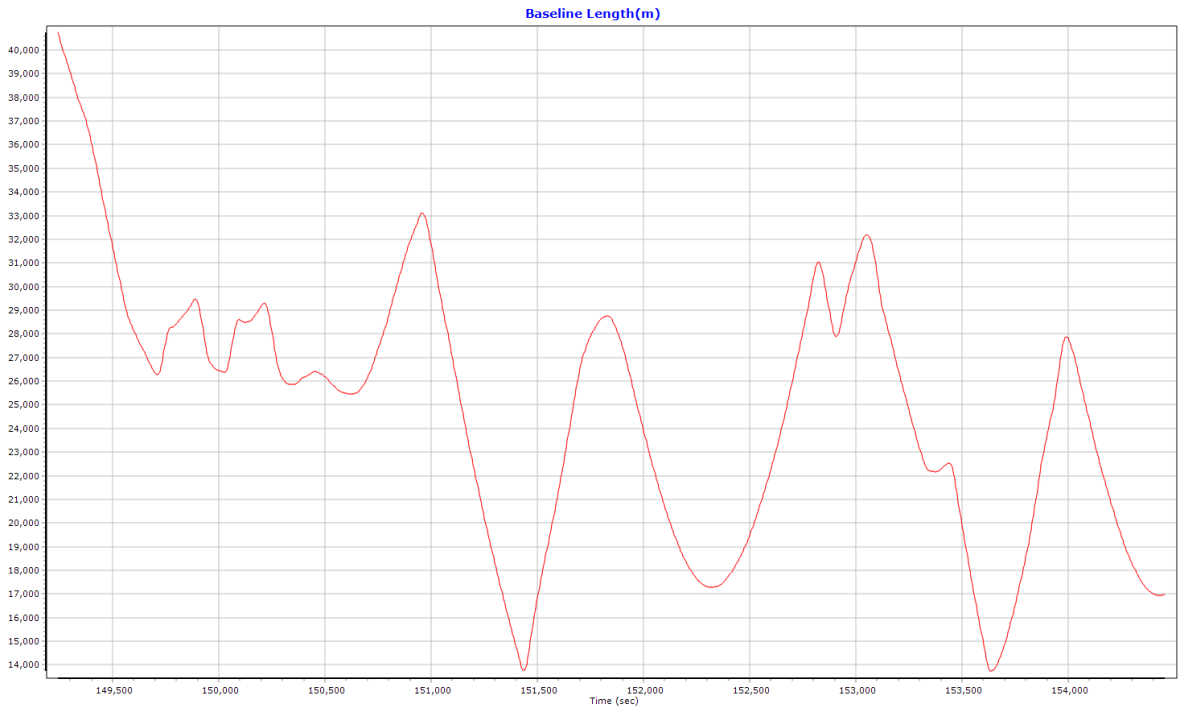
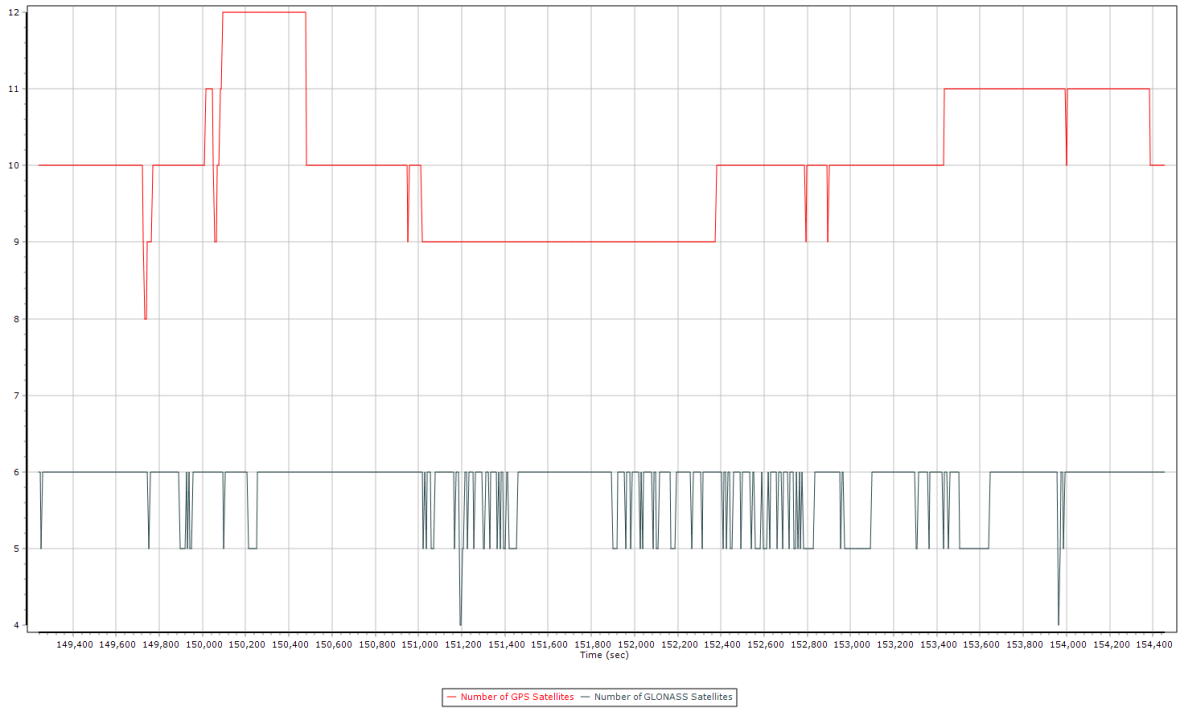
RBV19084B

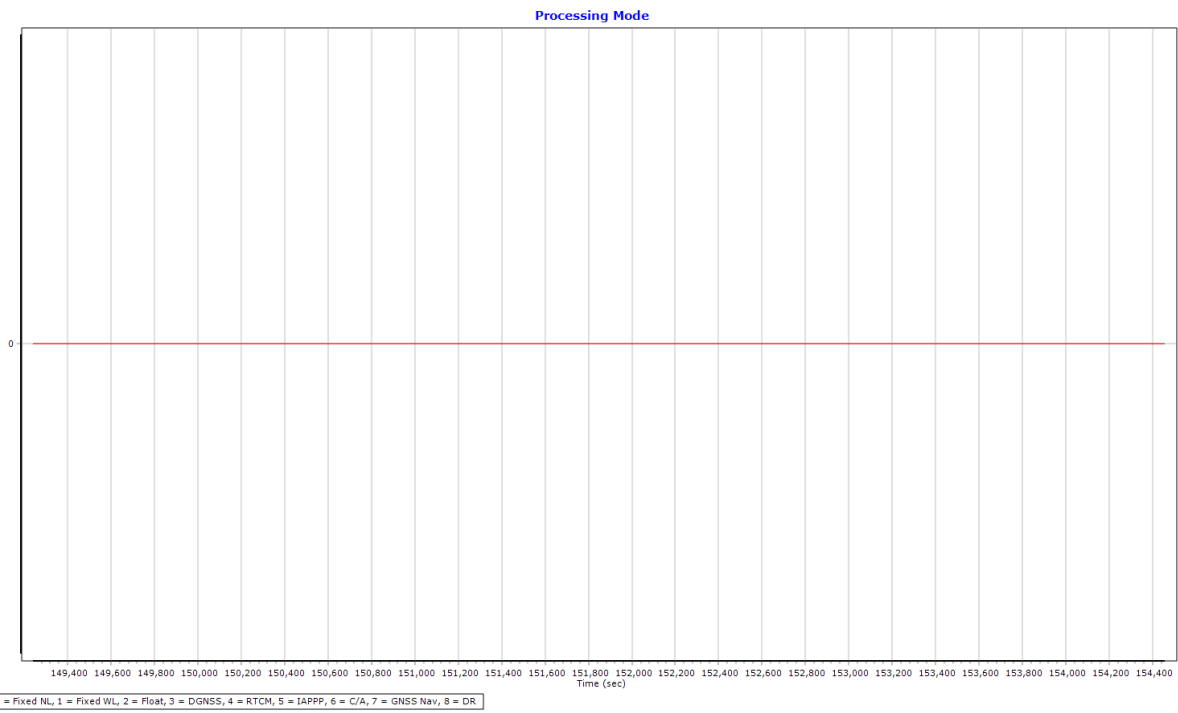
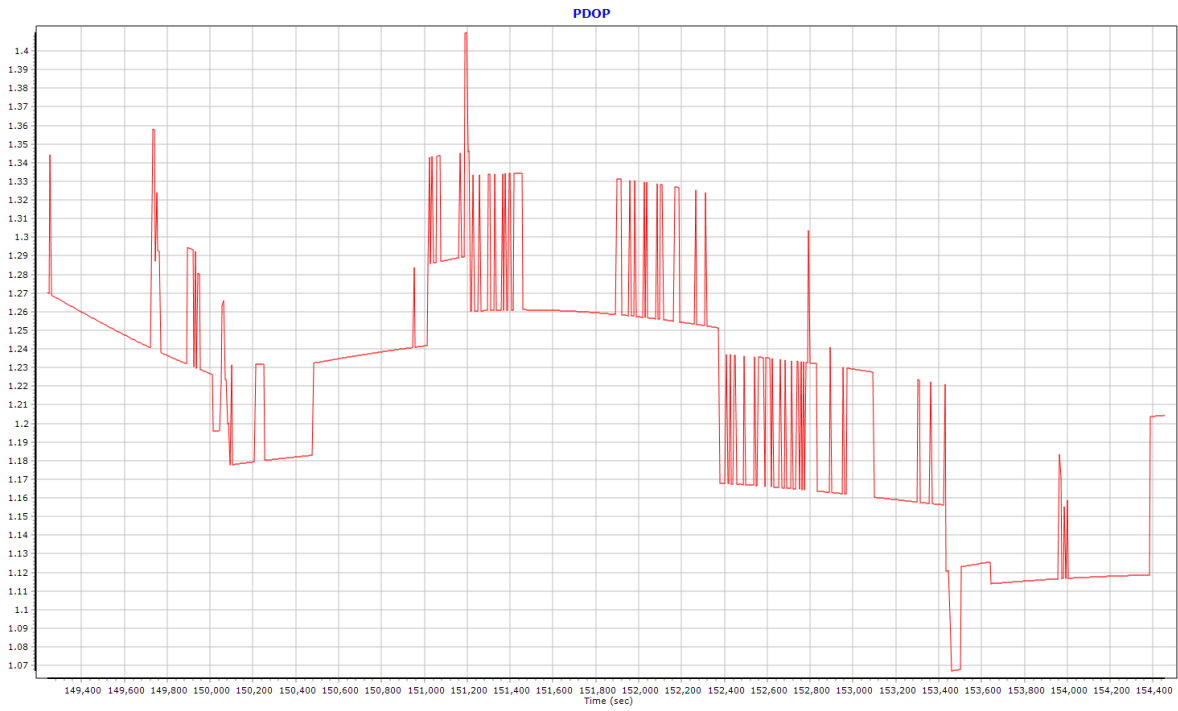




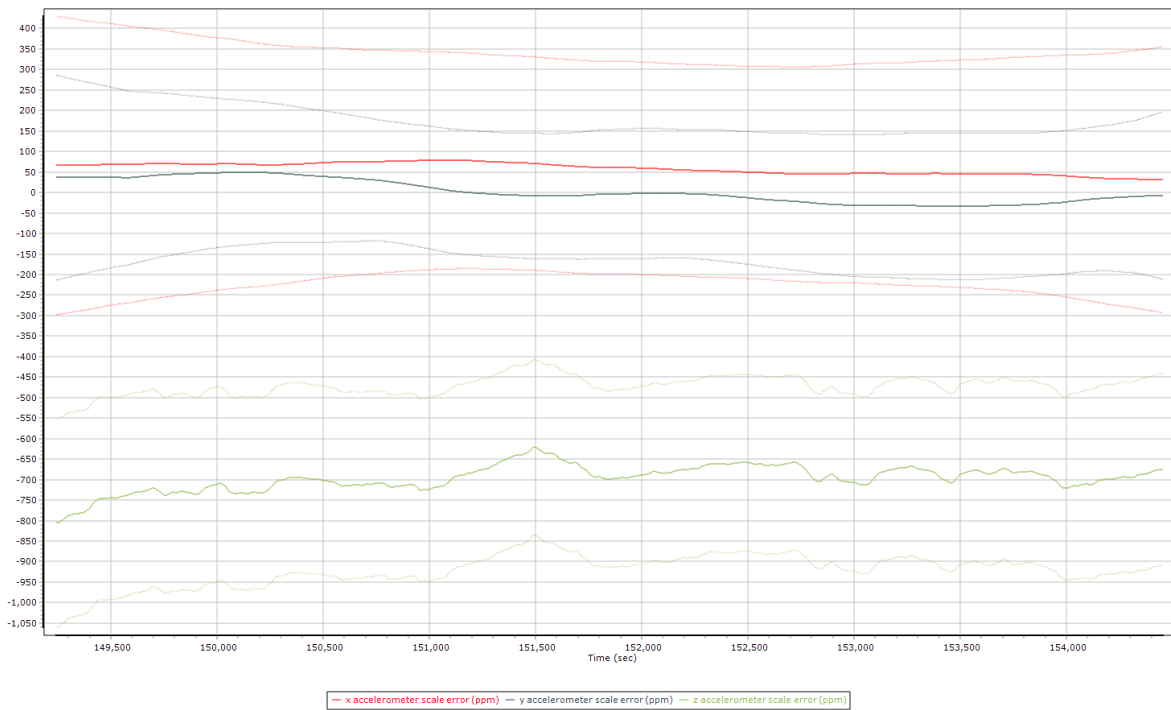
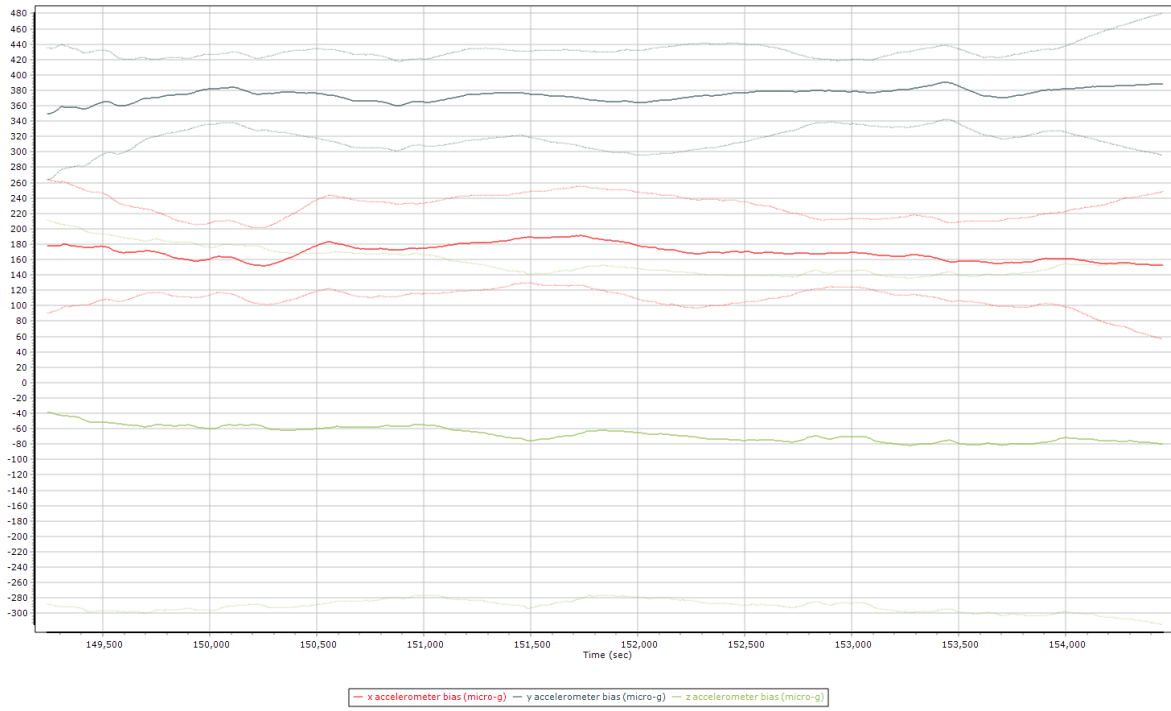


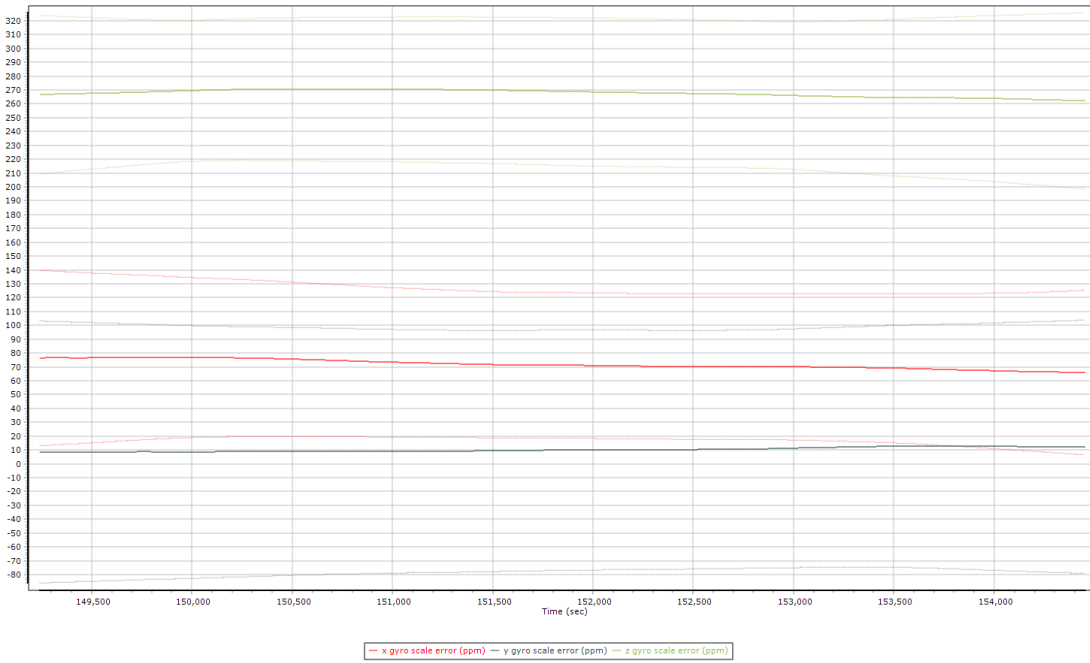
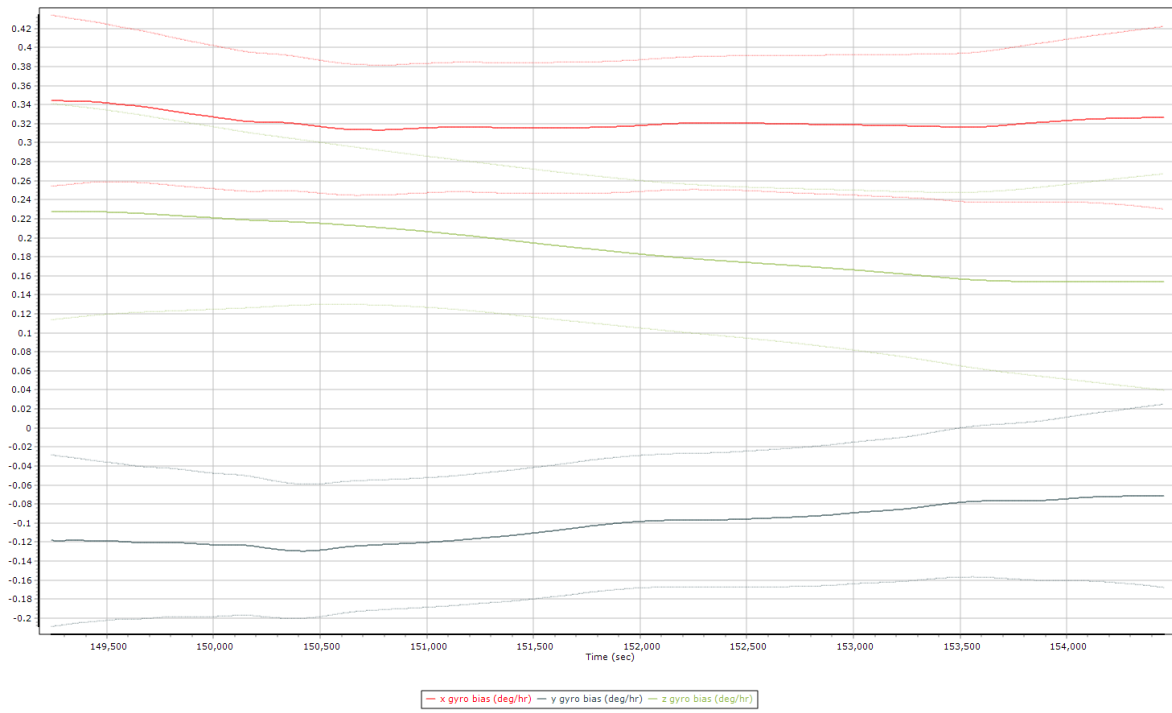




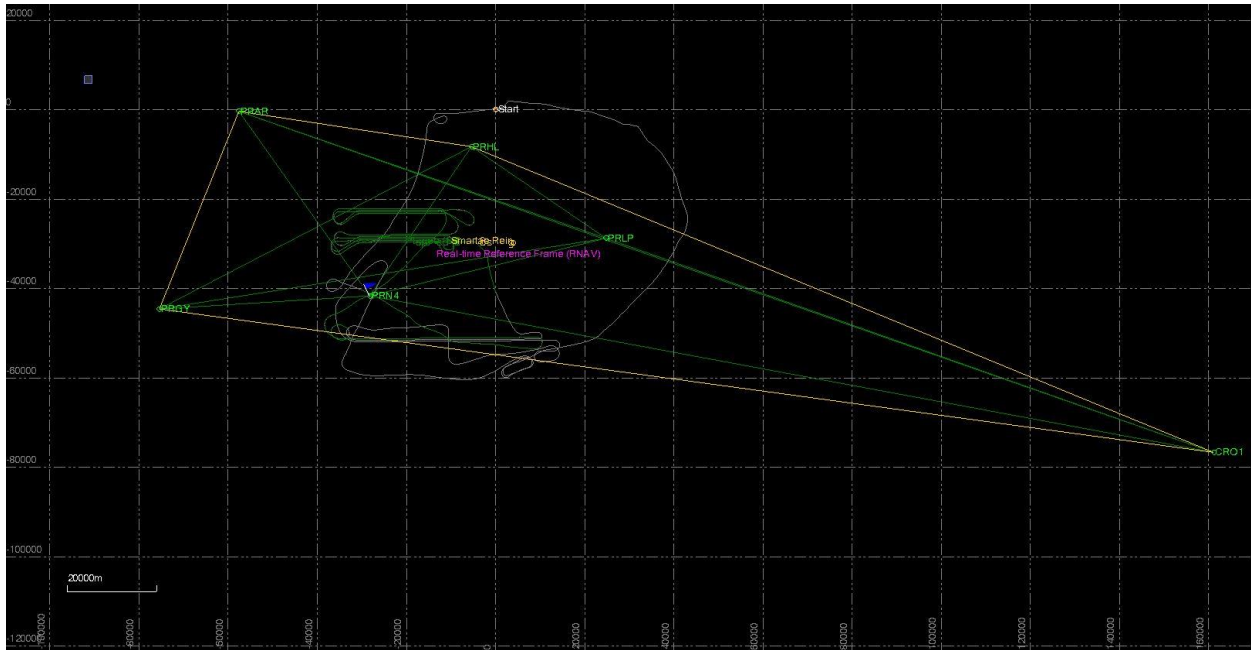


Sensor Errors





RBV19084B2



Project Settings

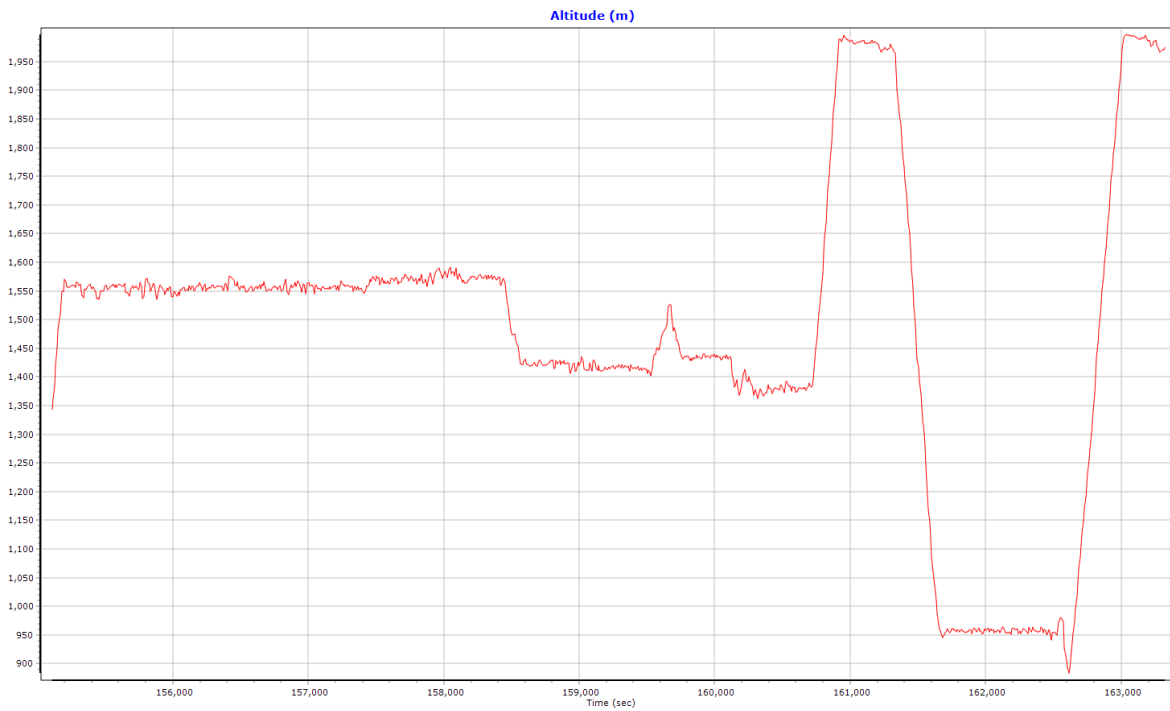
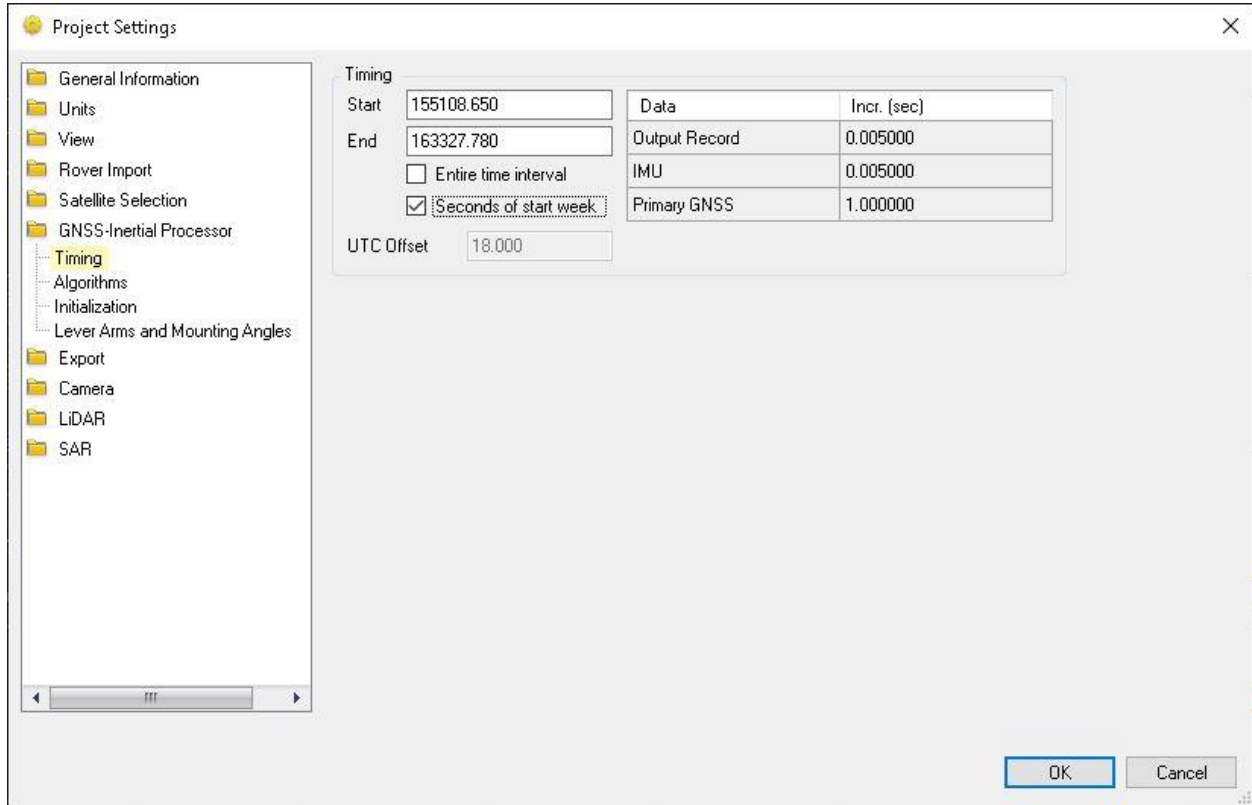
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LIDAR
- SAR

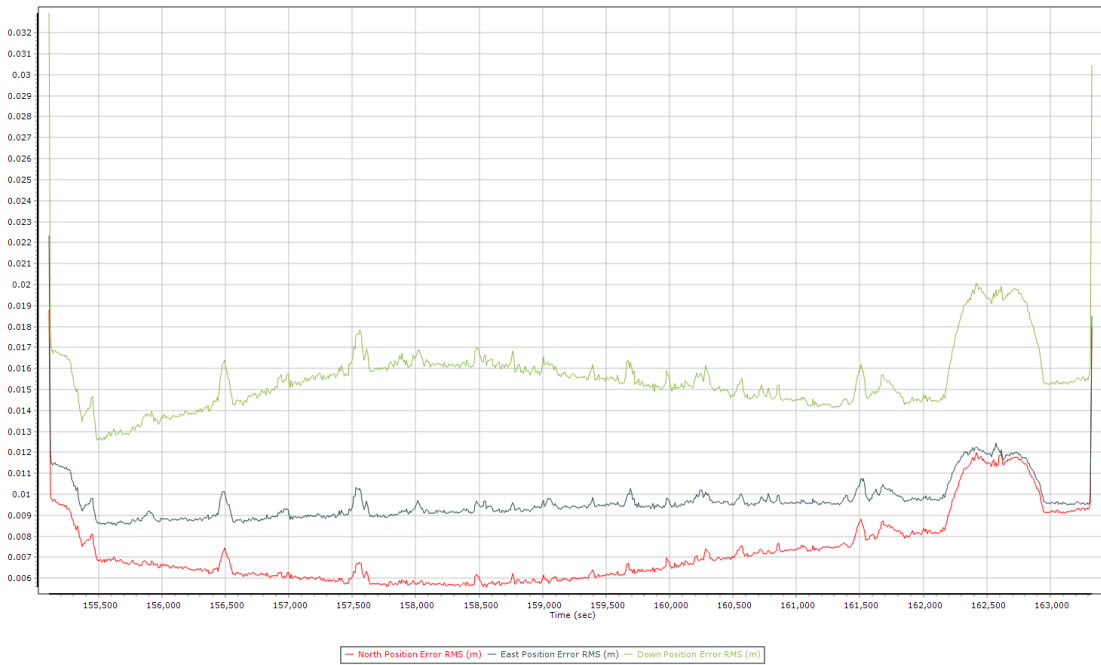
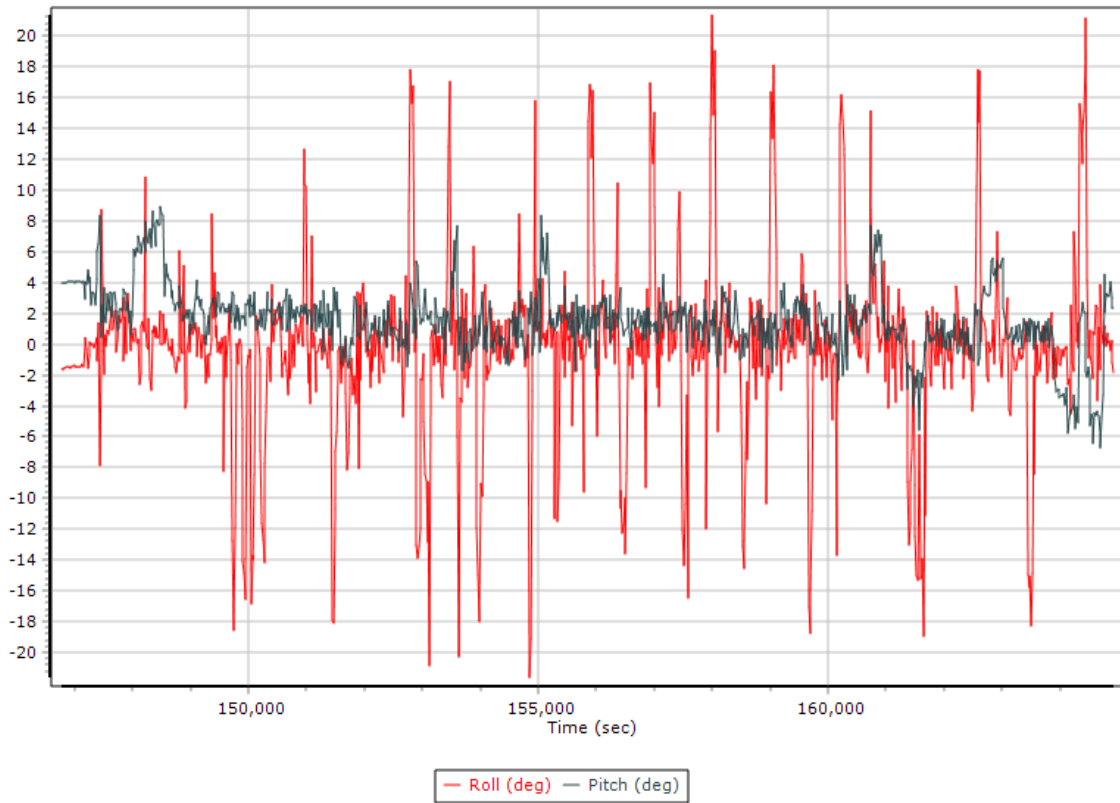
Reference to IMU Lever Arm	Reference to IMU Mounting Angles
X: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

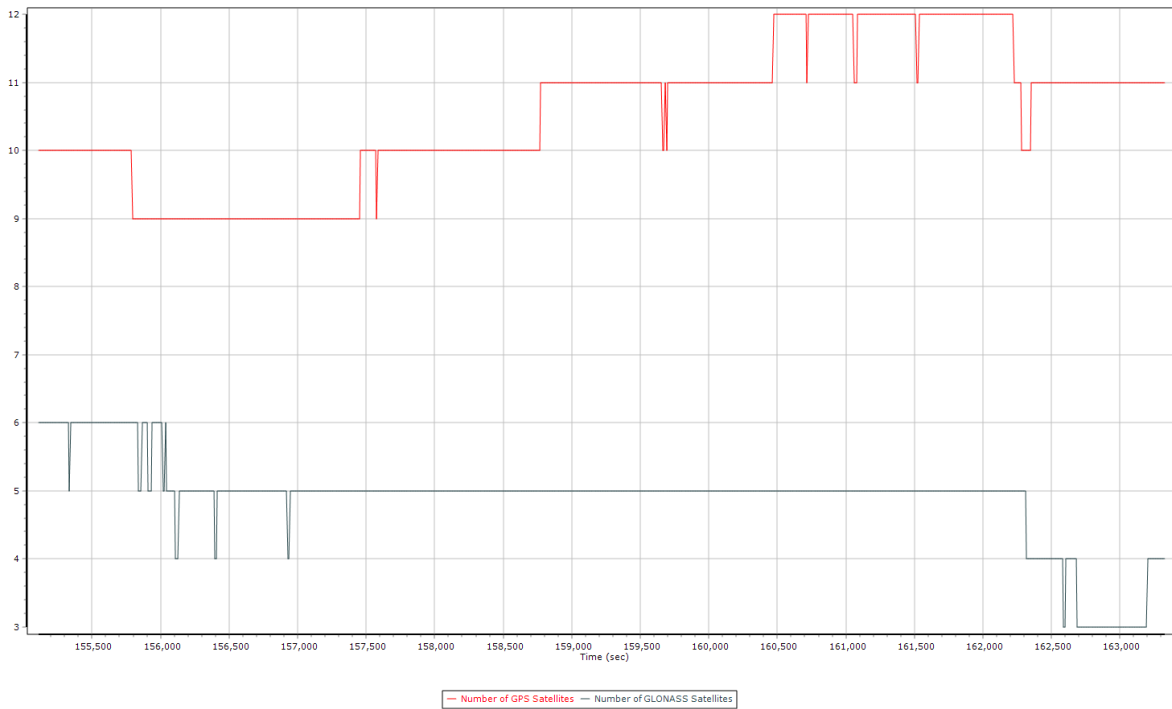
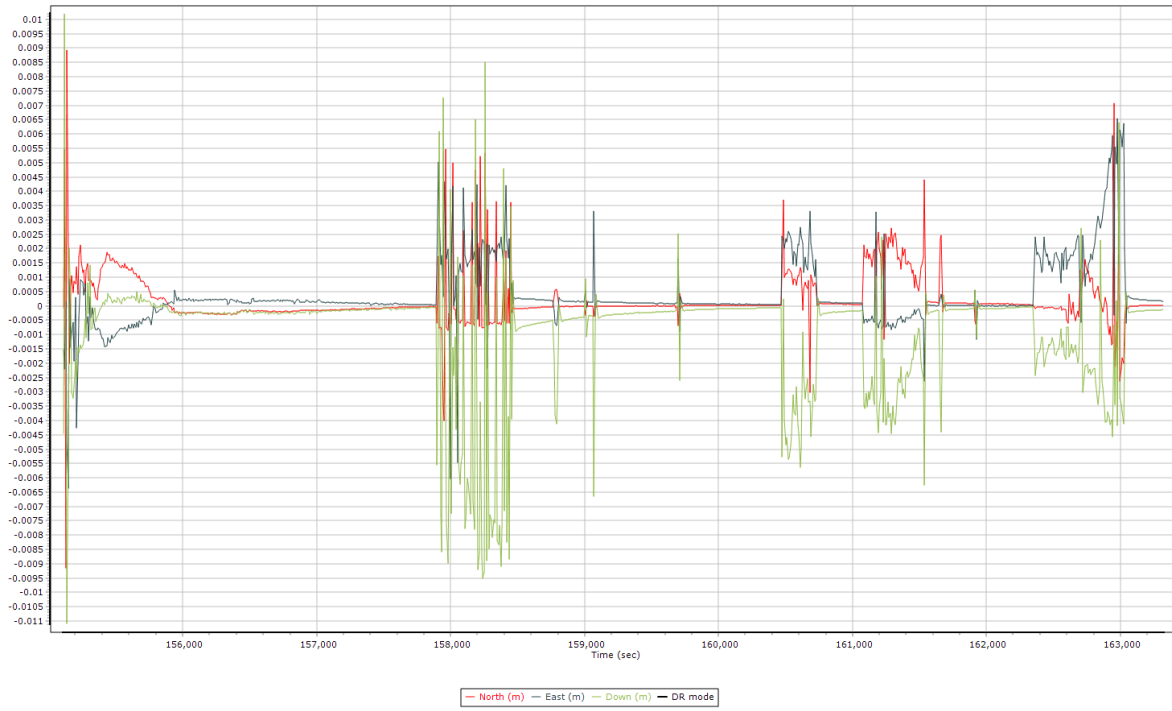
Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 m	Z: 0.000 deg

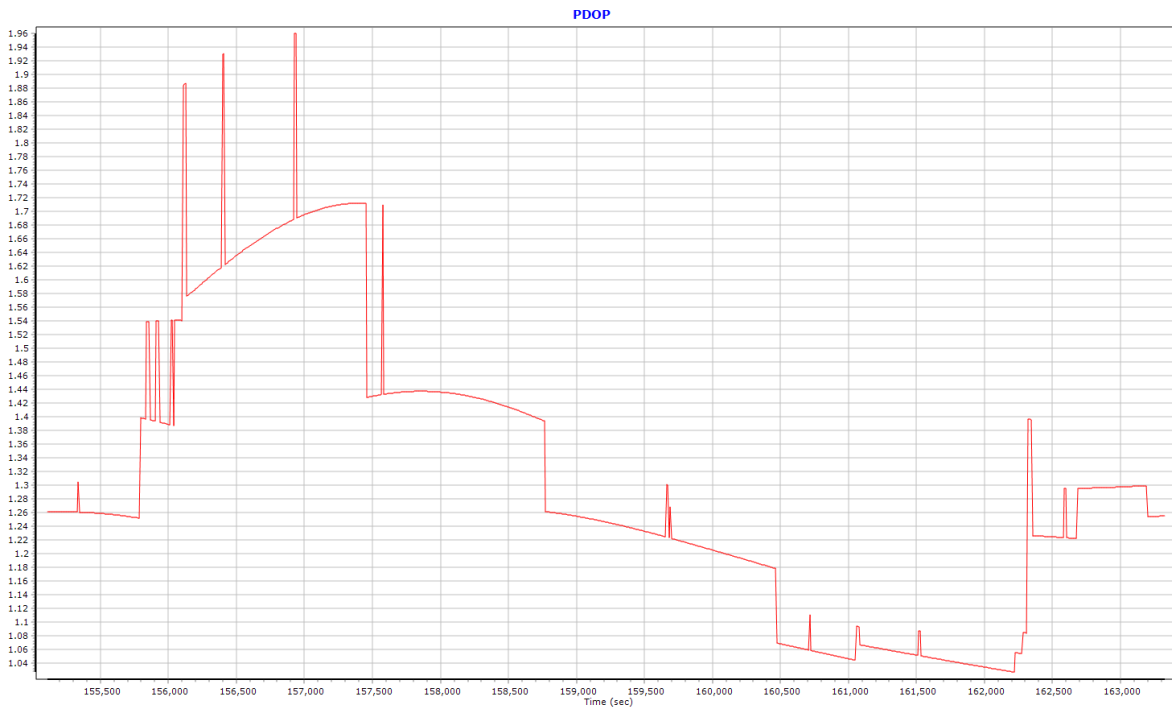
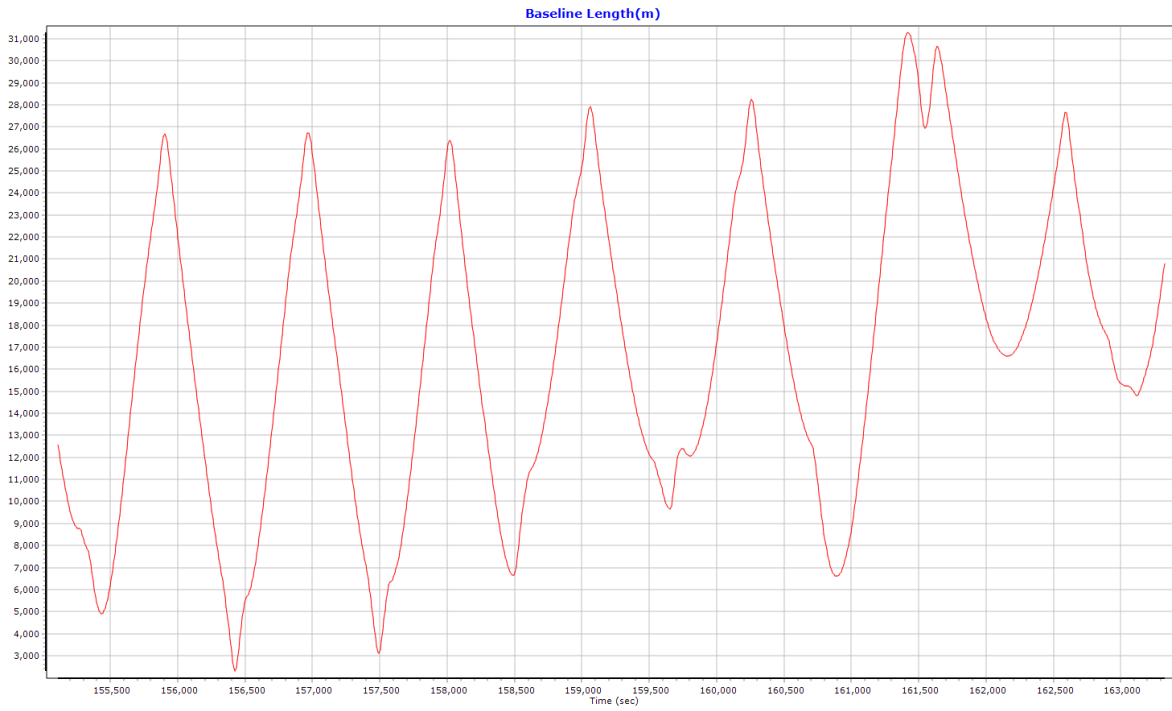
Standard Deviation: <3cm 10cm 50cm 1m 10m

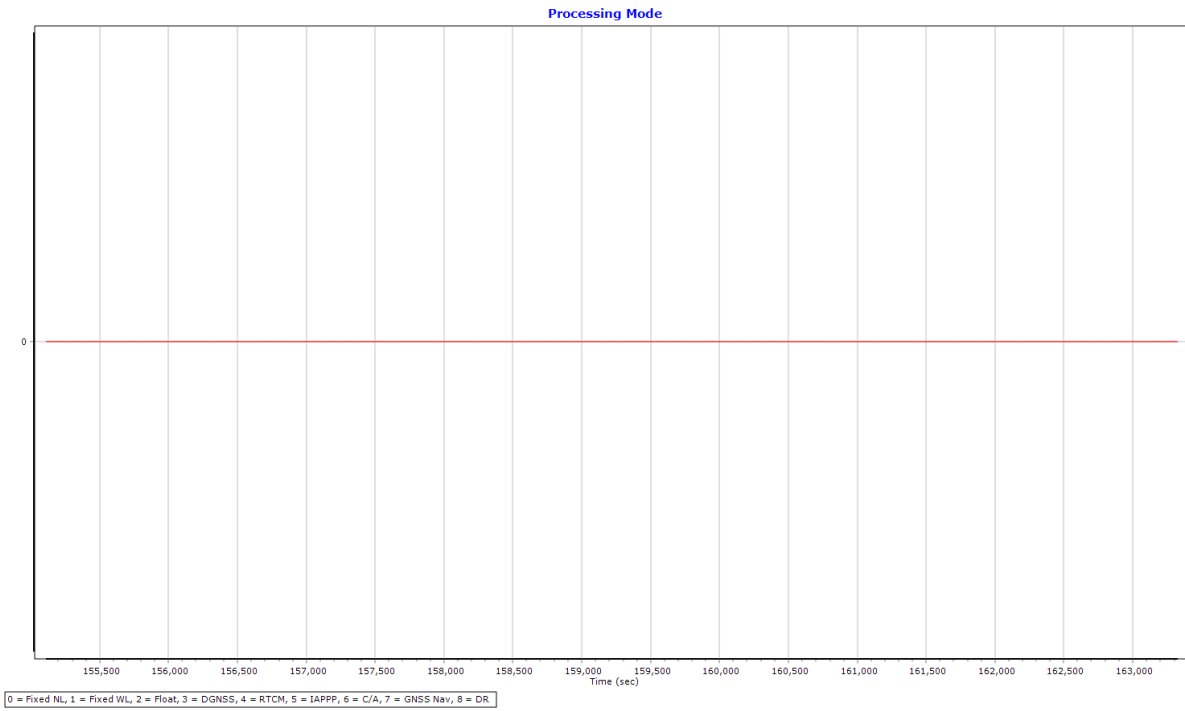
OK Cancel





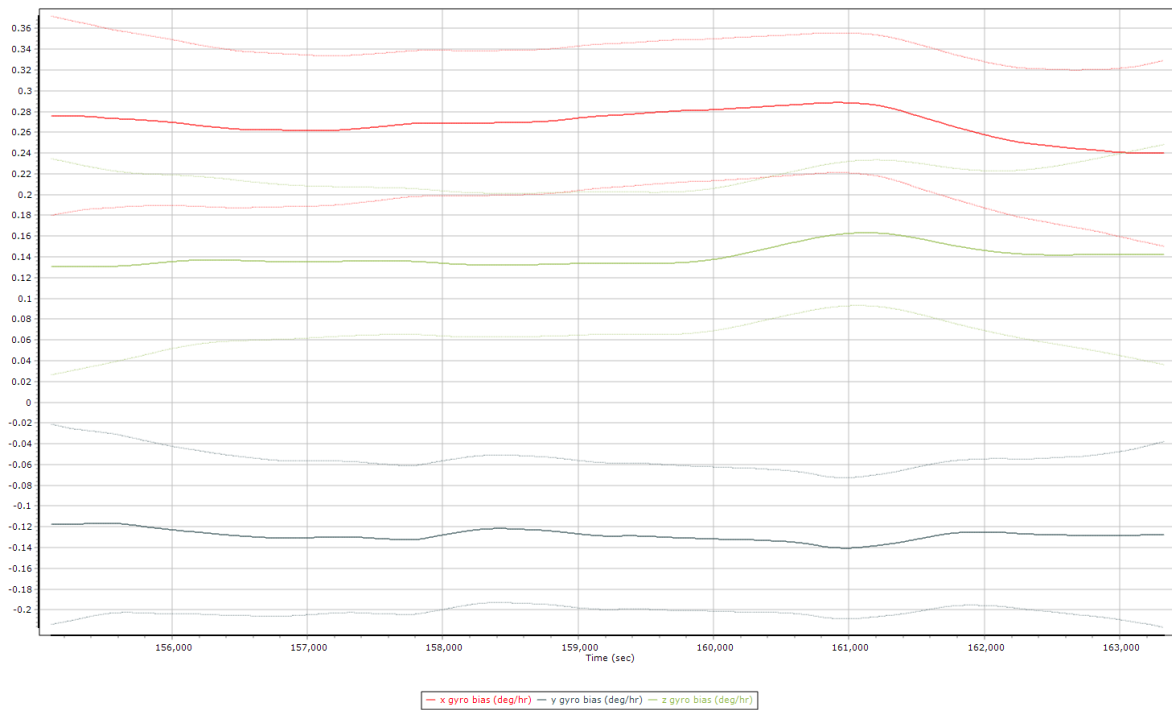
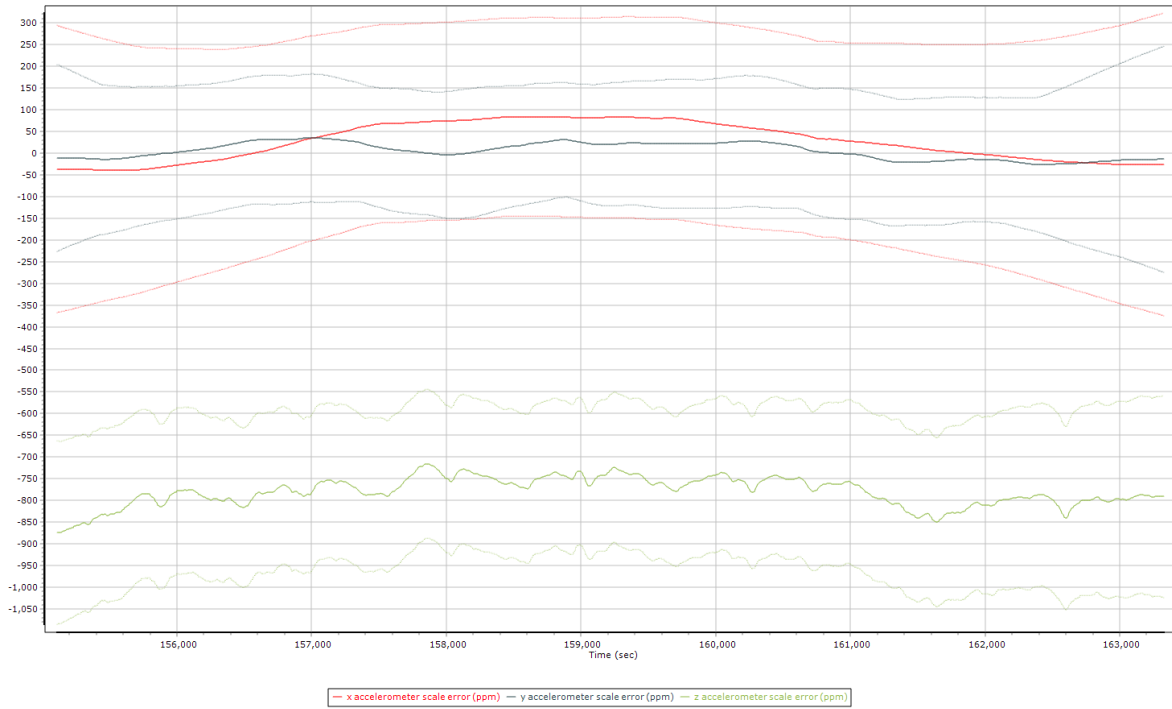


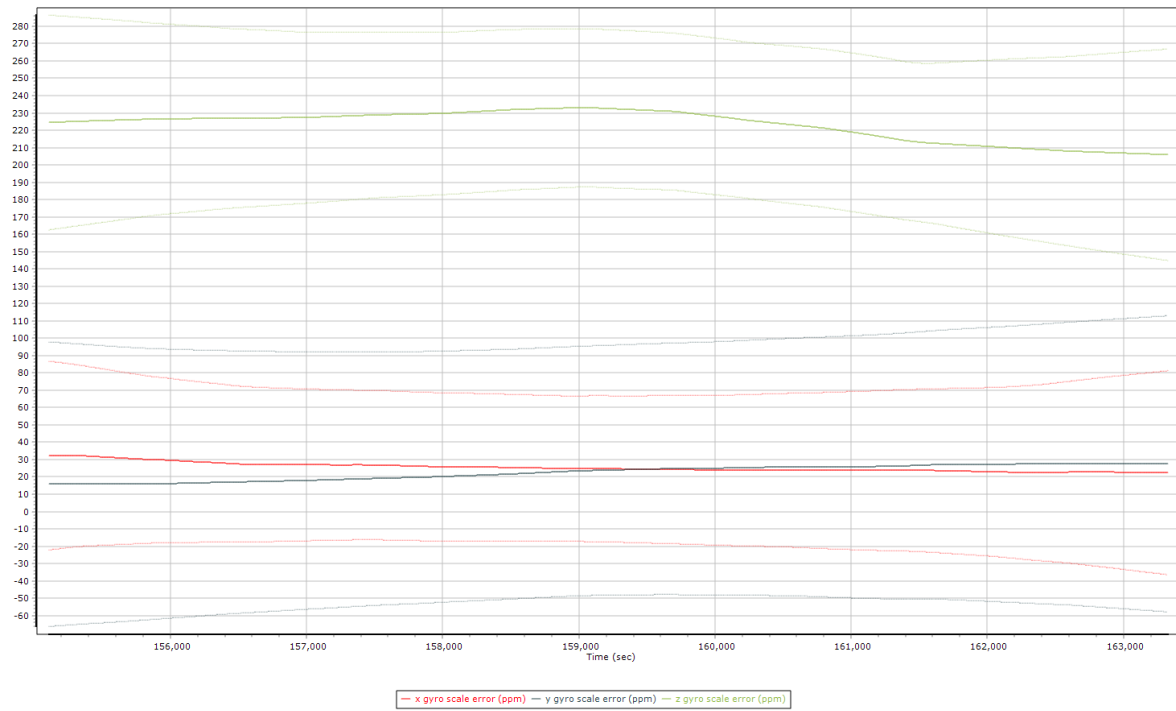




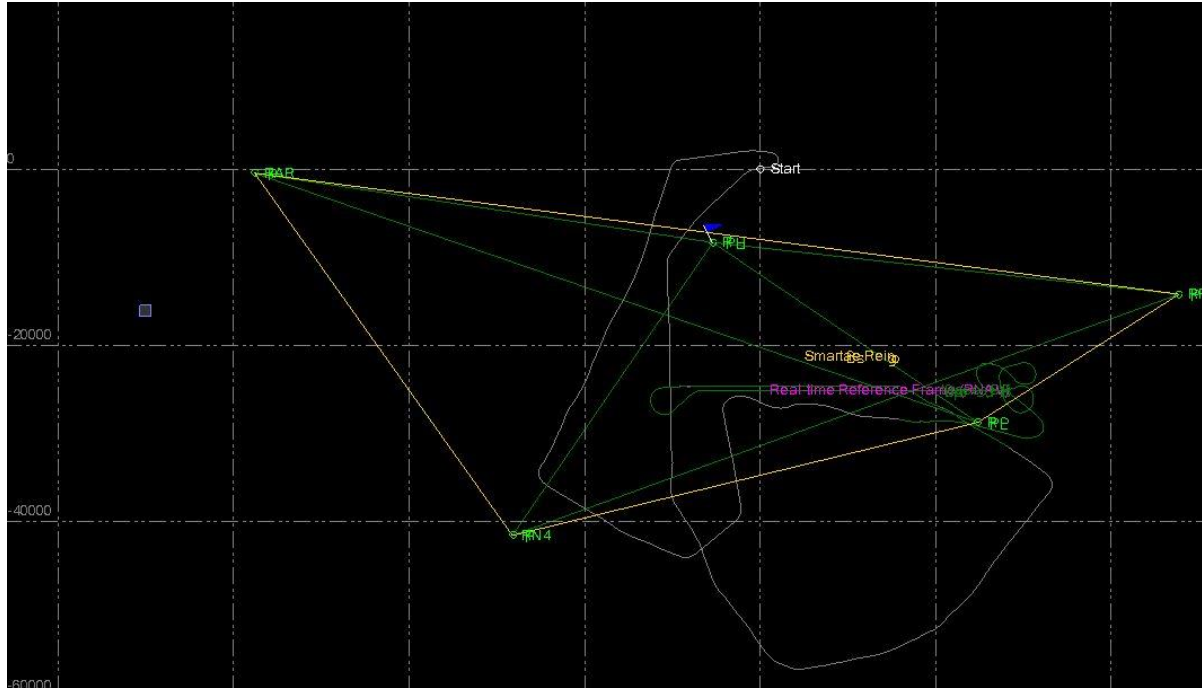
Sensor Errors

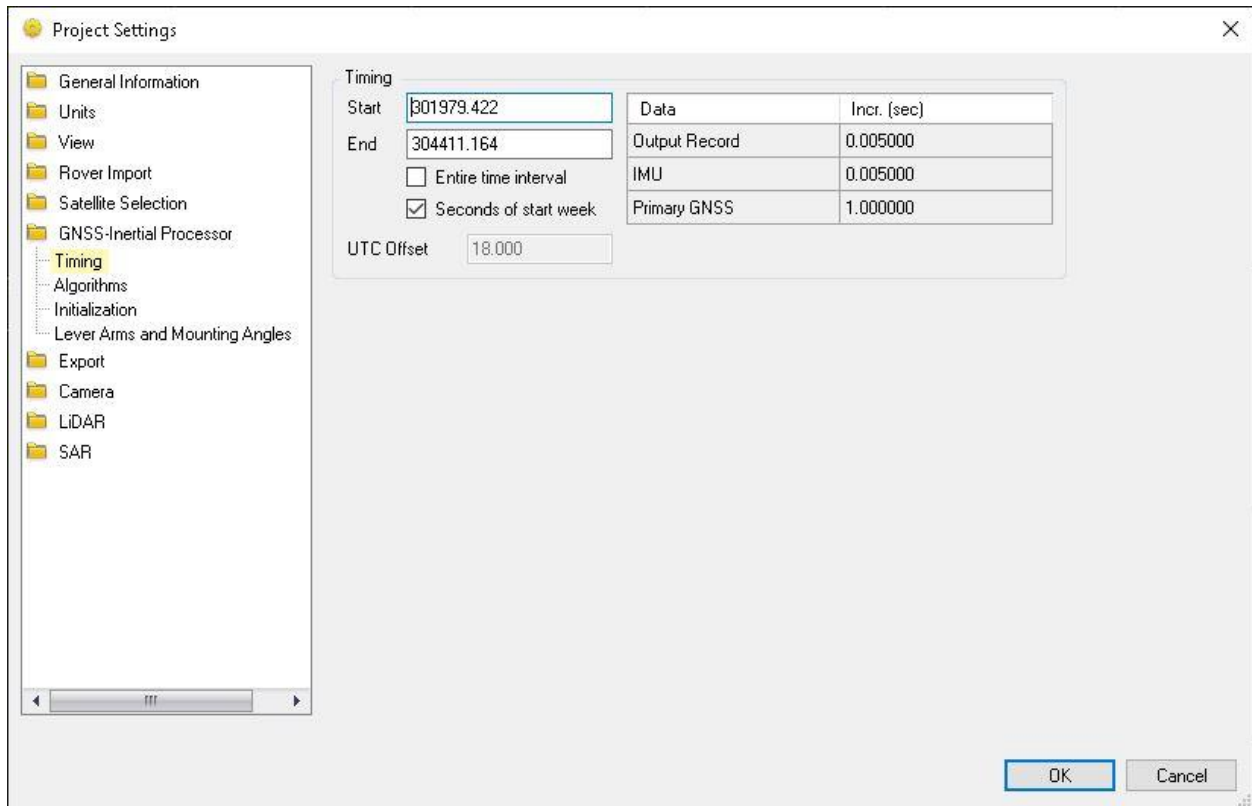
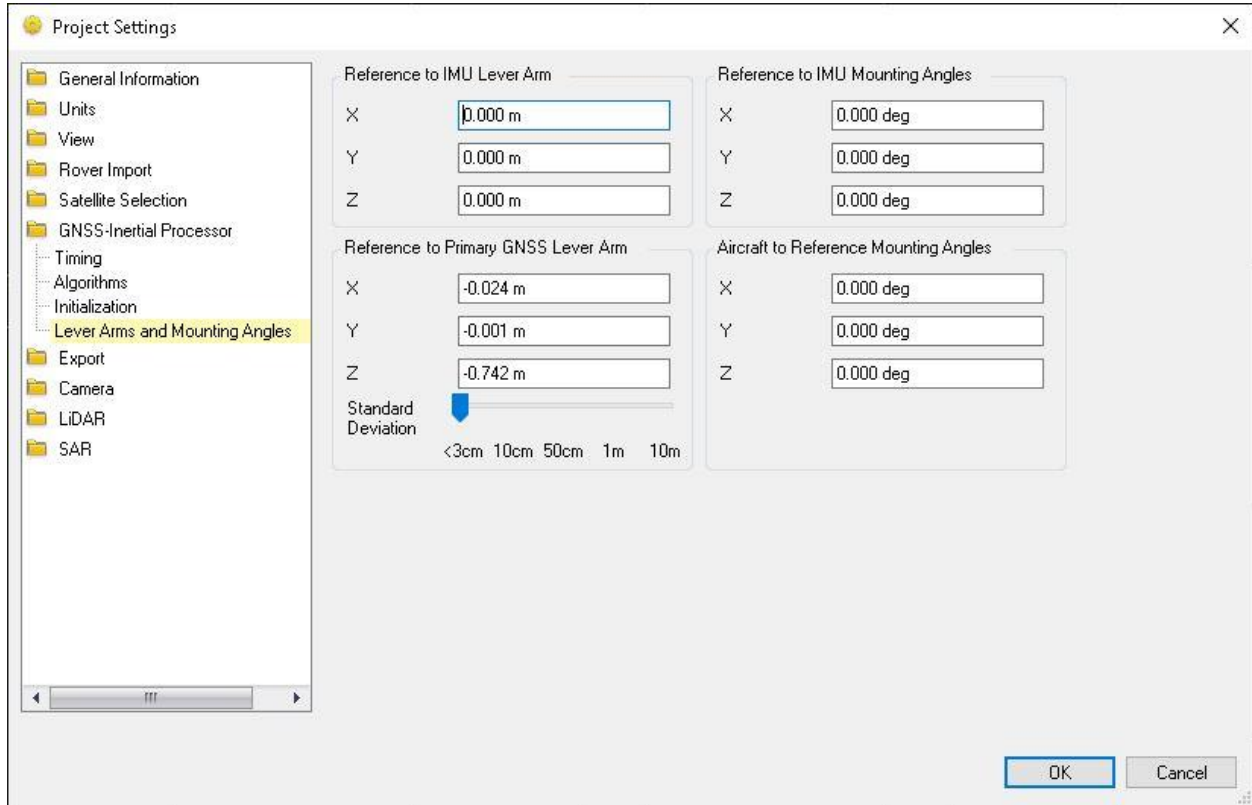


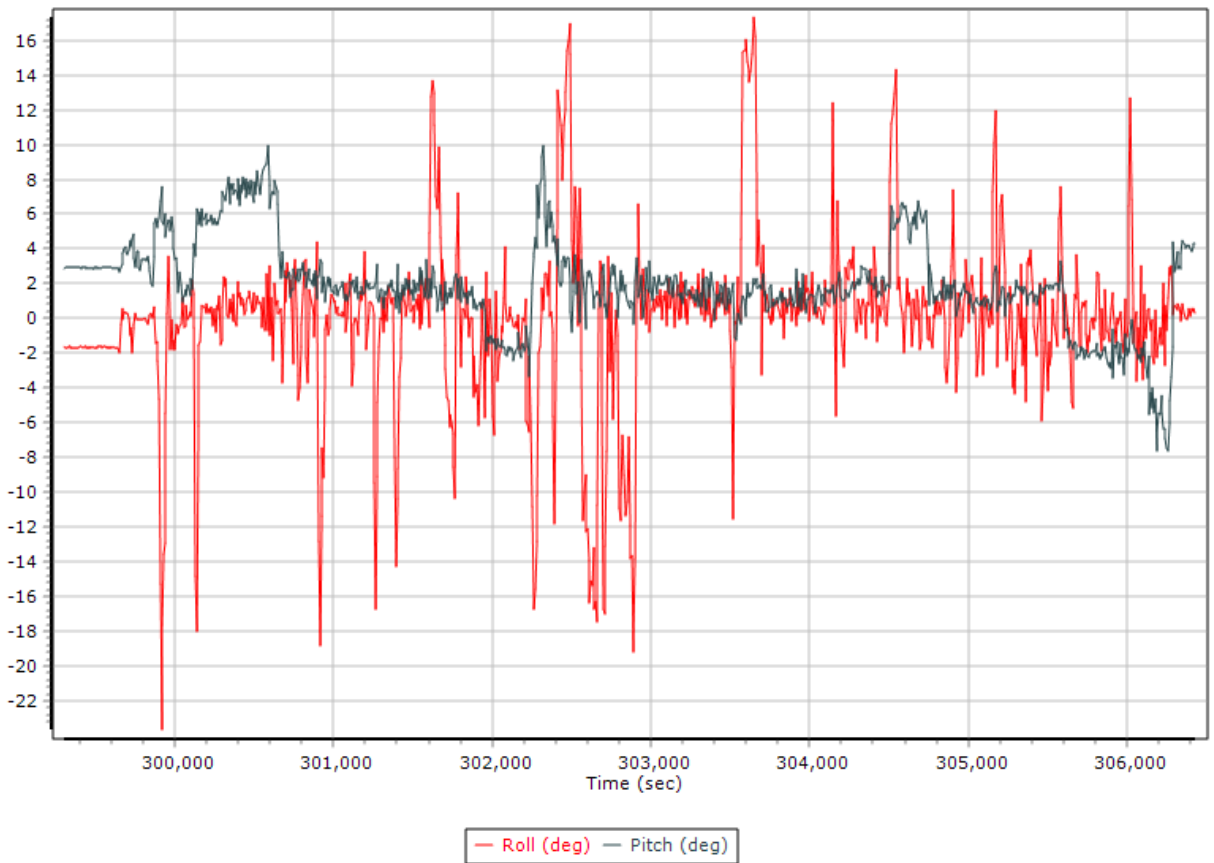
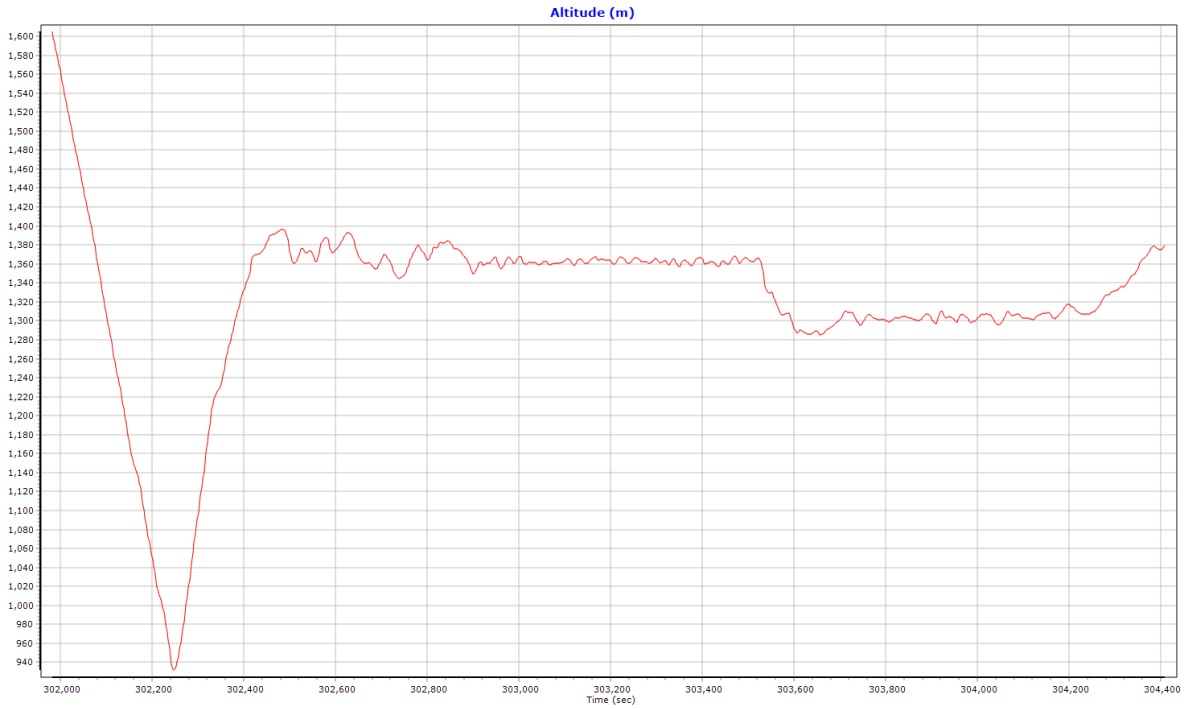


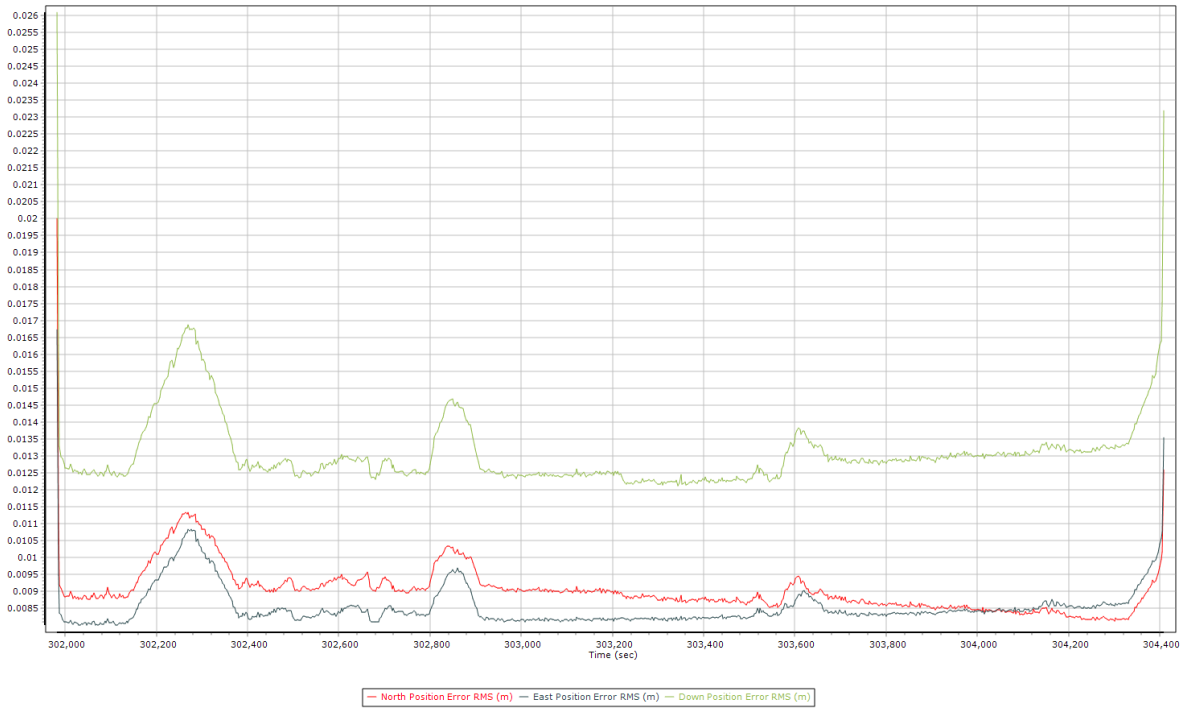


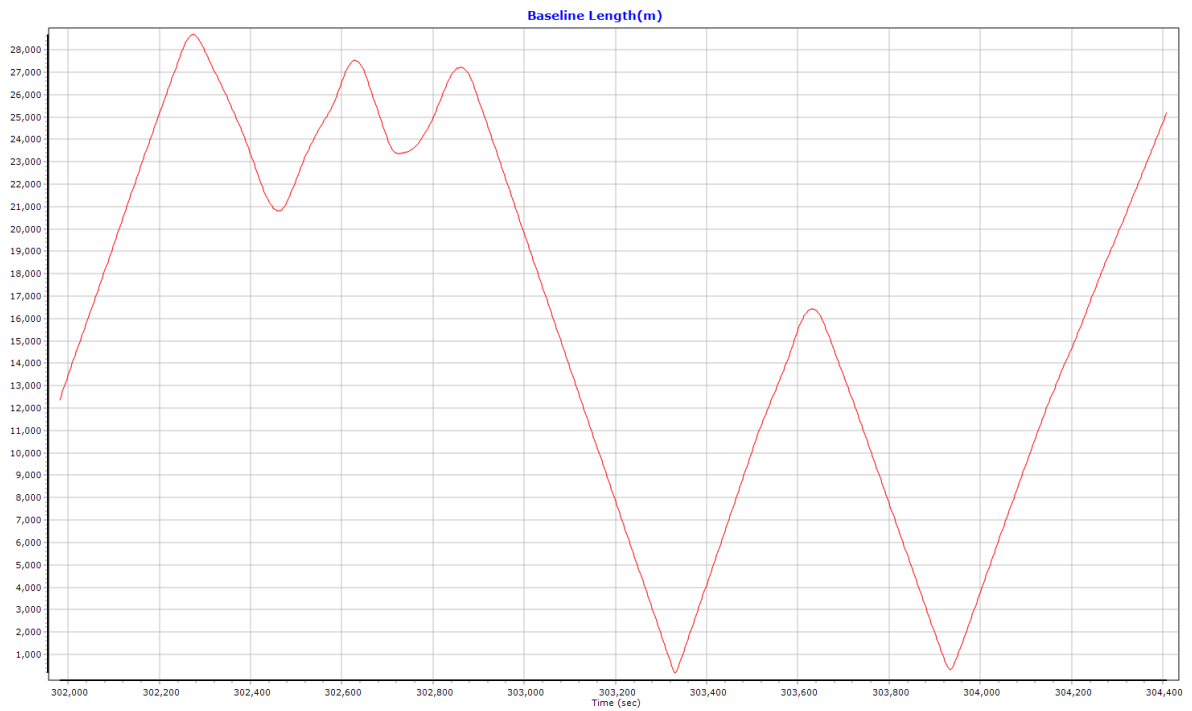
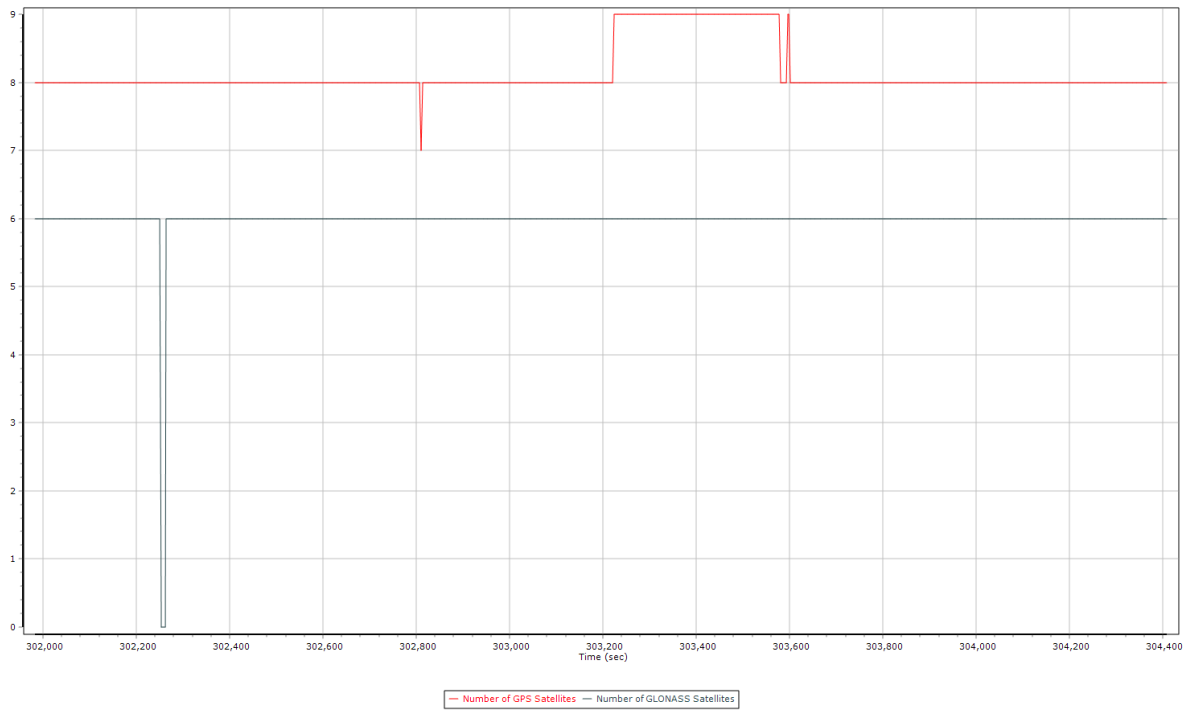
RBV19086A

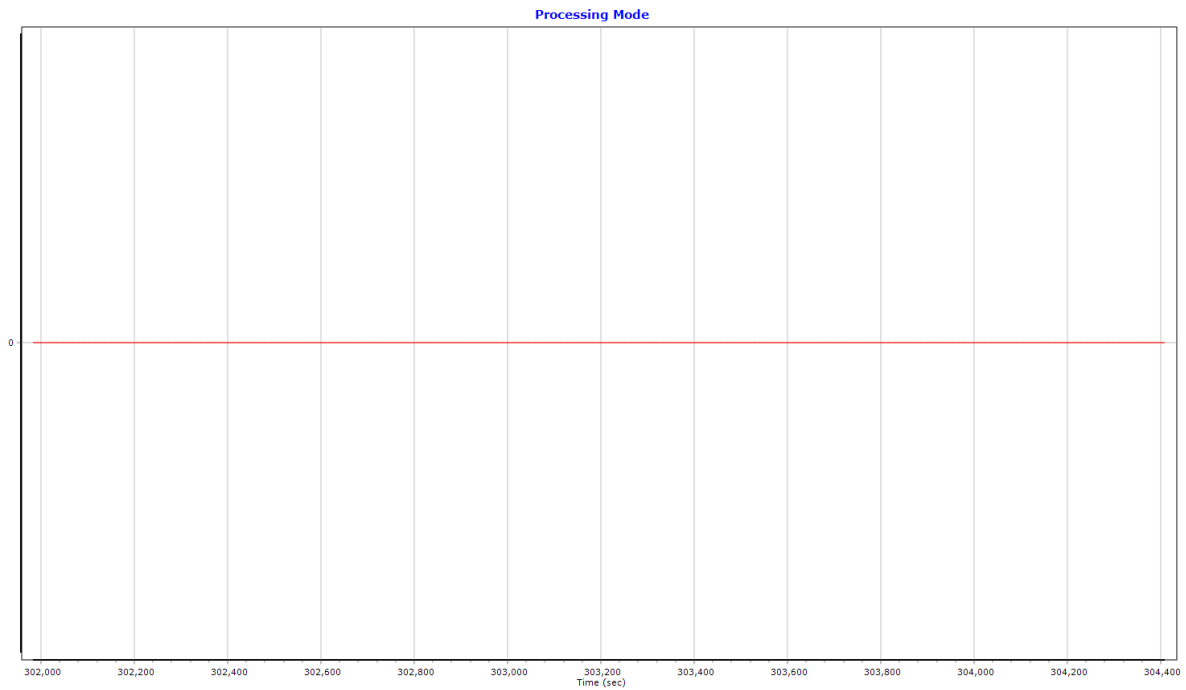
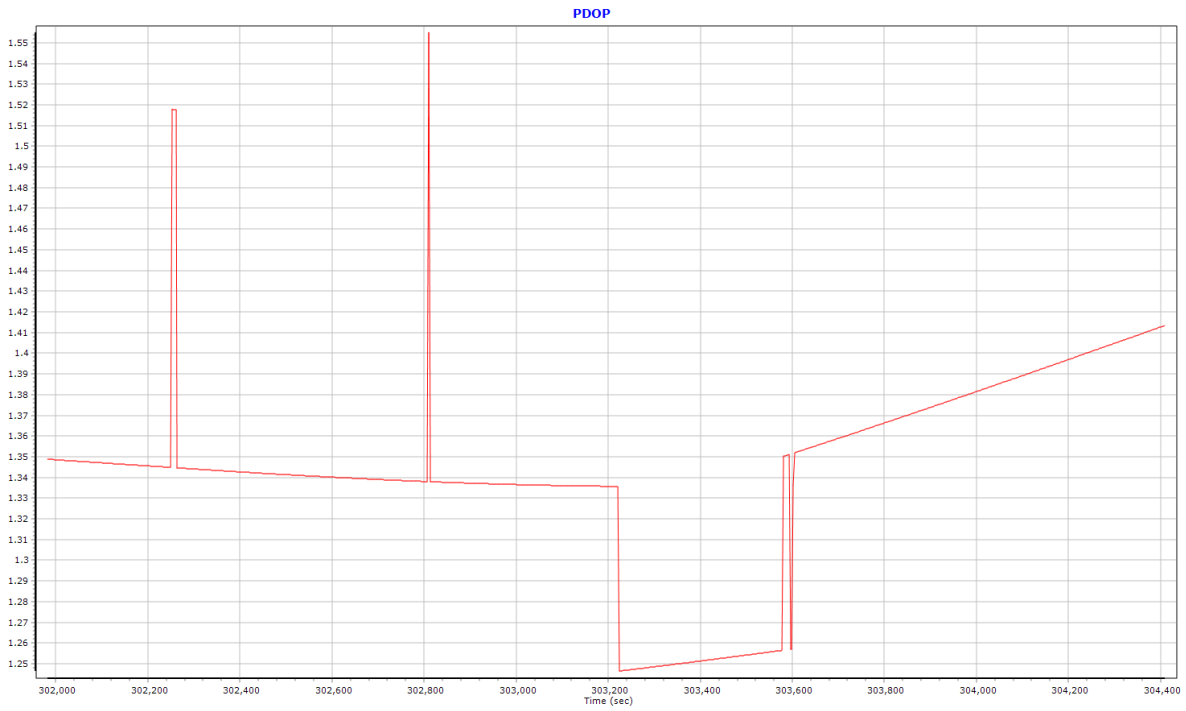






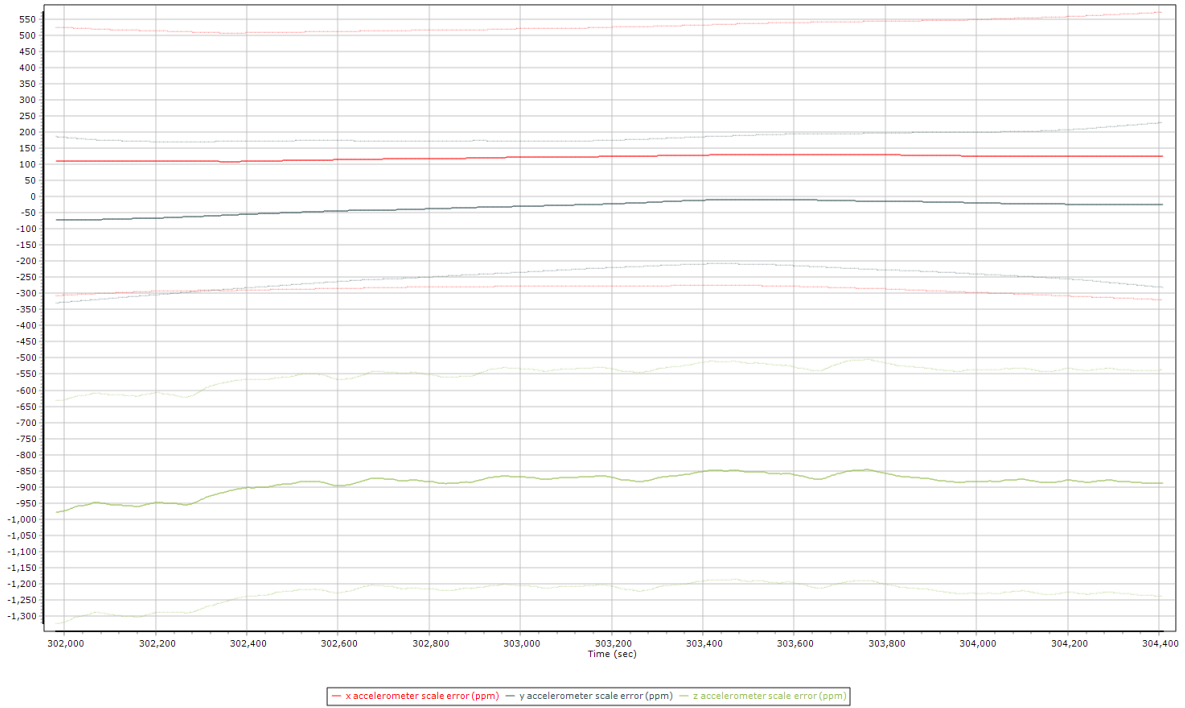
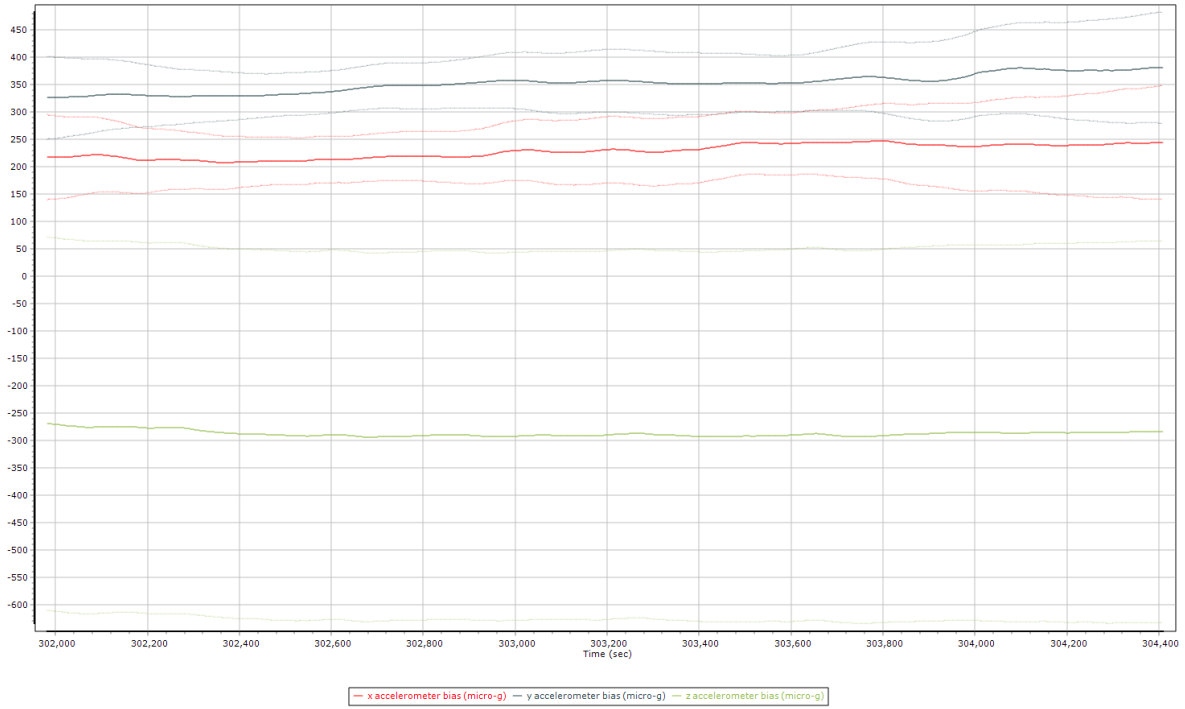


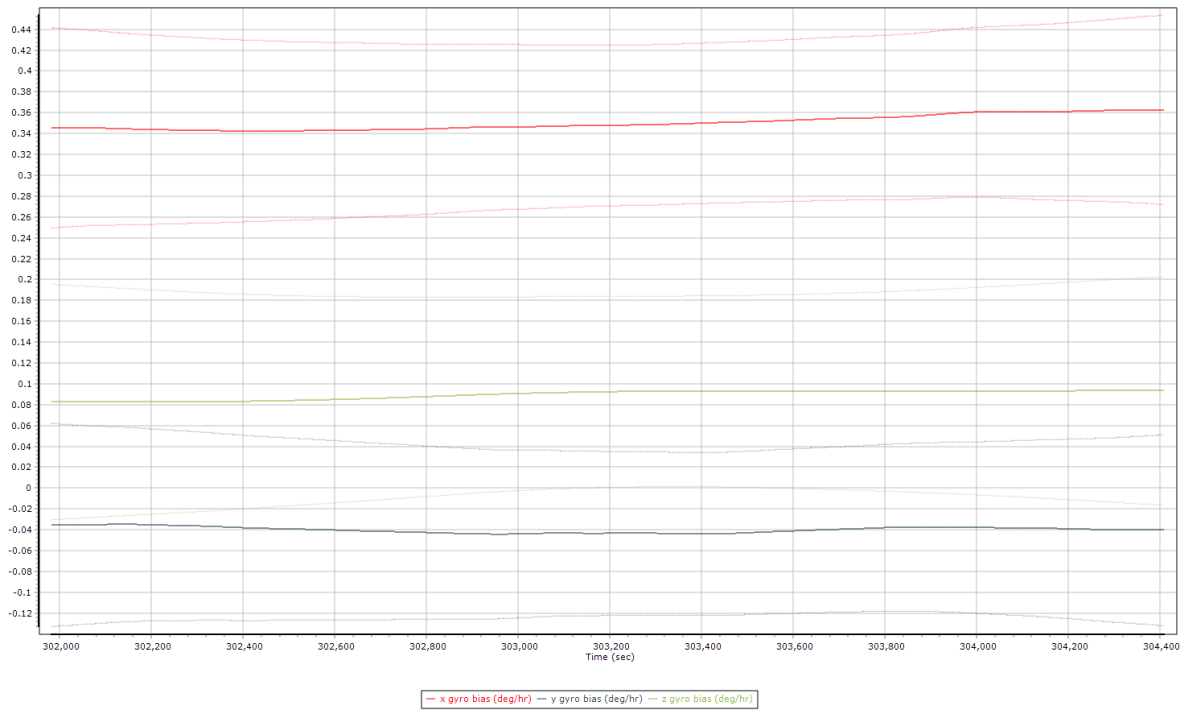




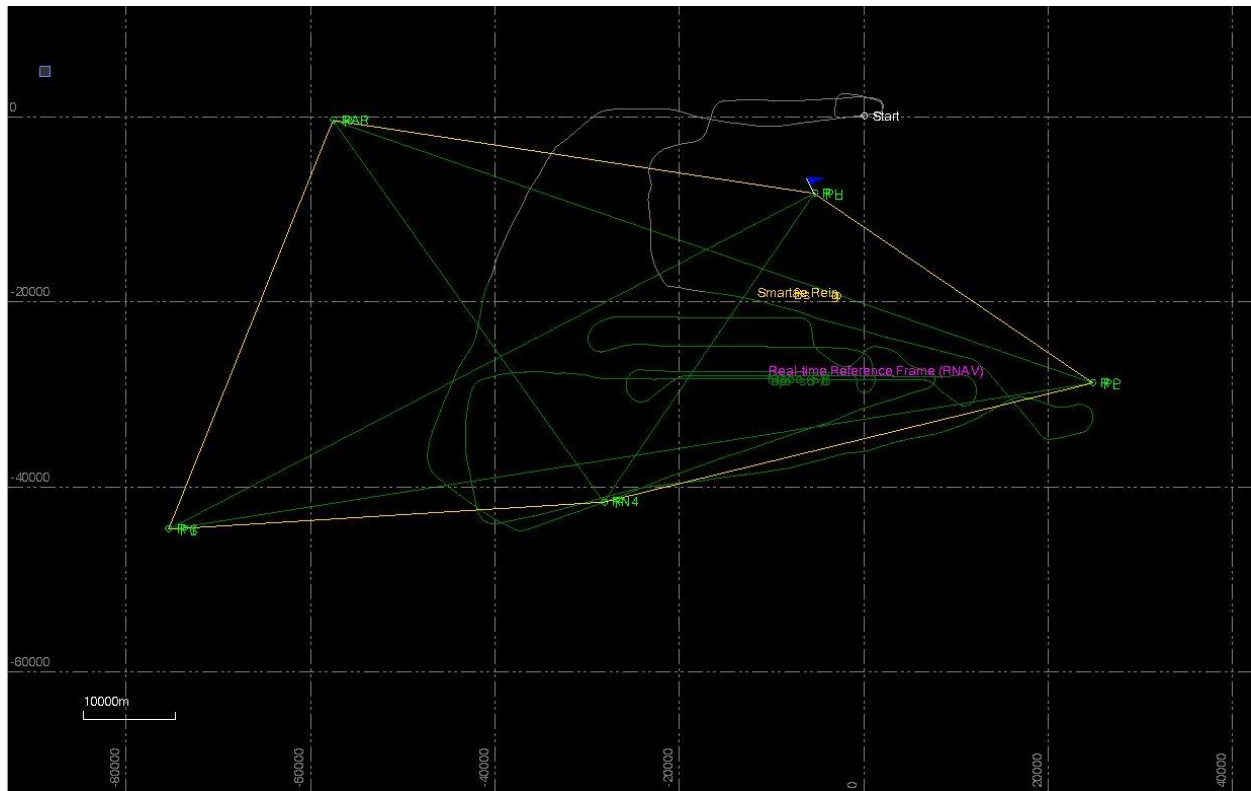
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





RBV19087A



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: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 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

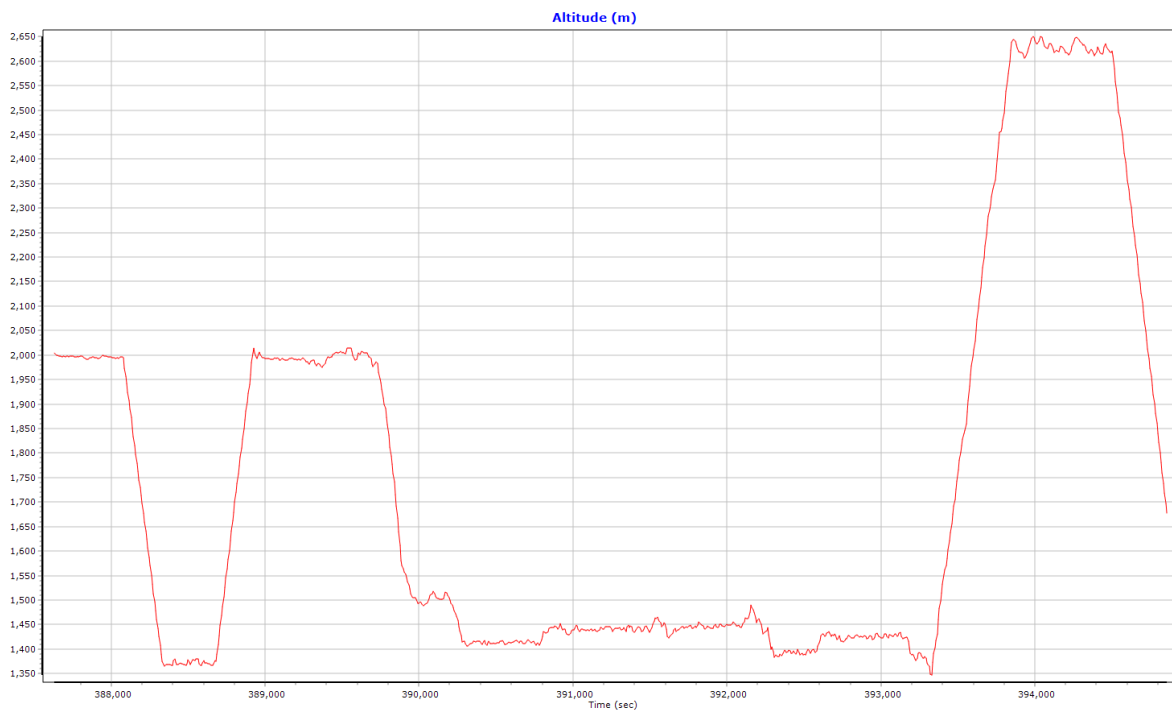
Start: 387629.117
End: 394858.337

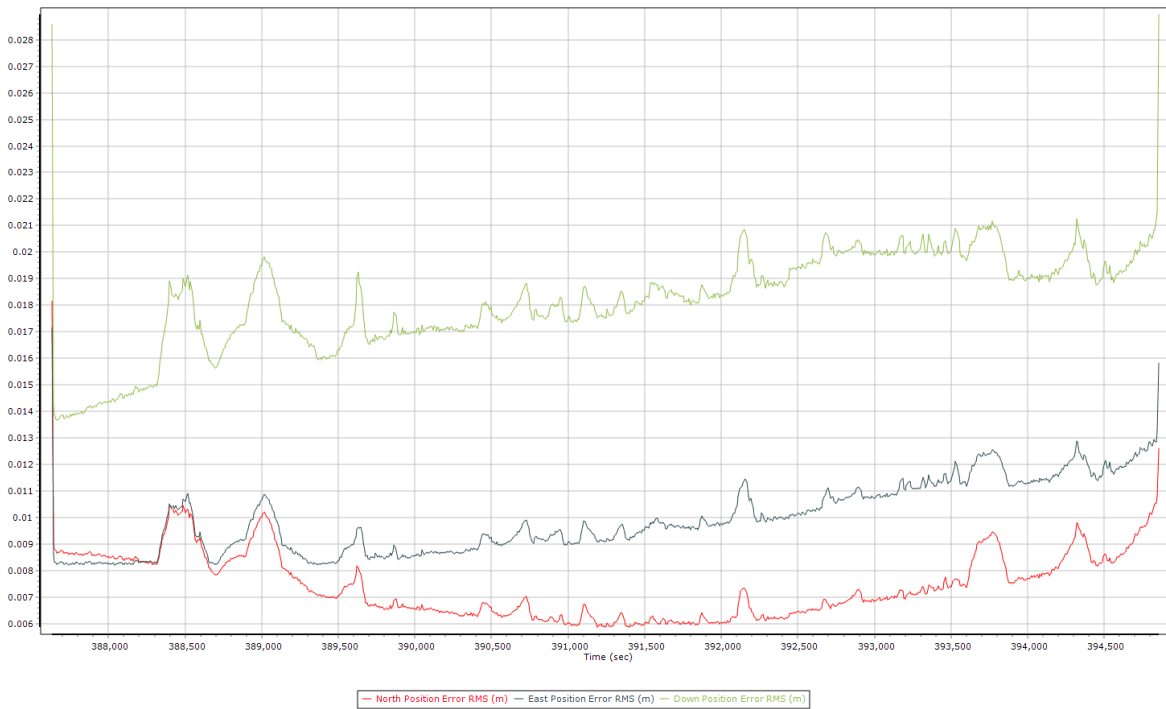
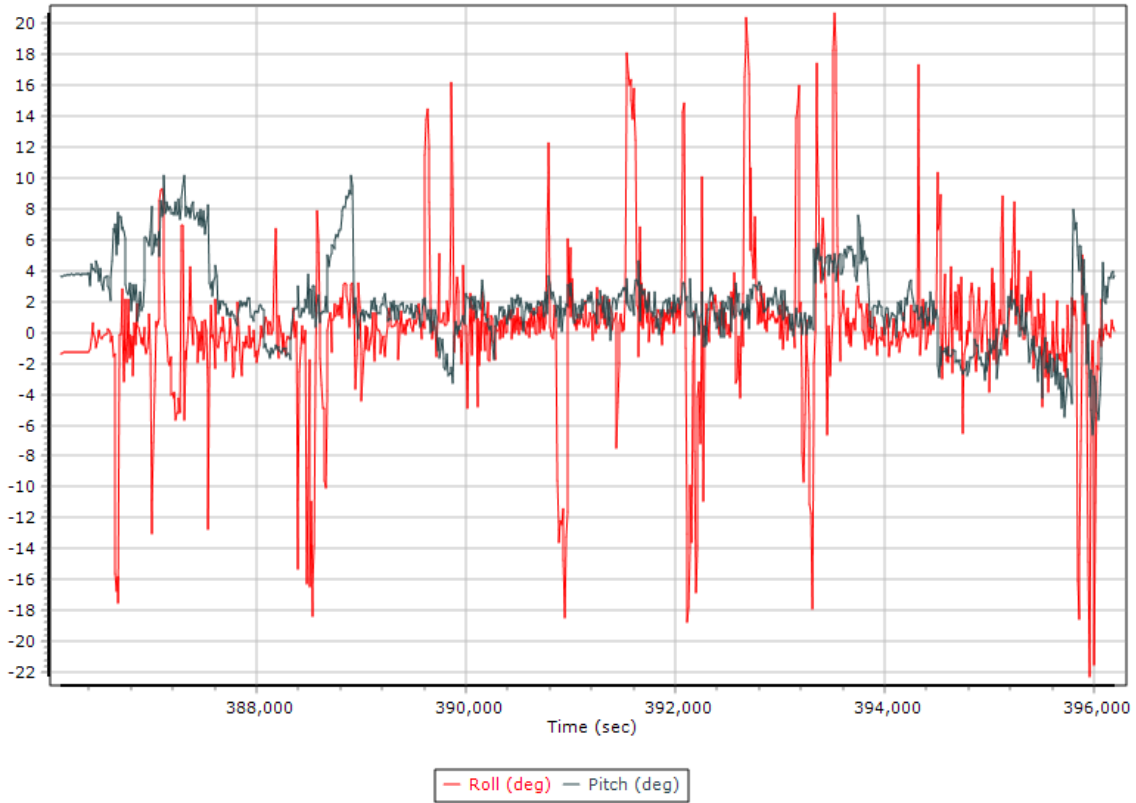
Entire time interval
 Seconds of start week

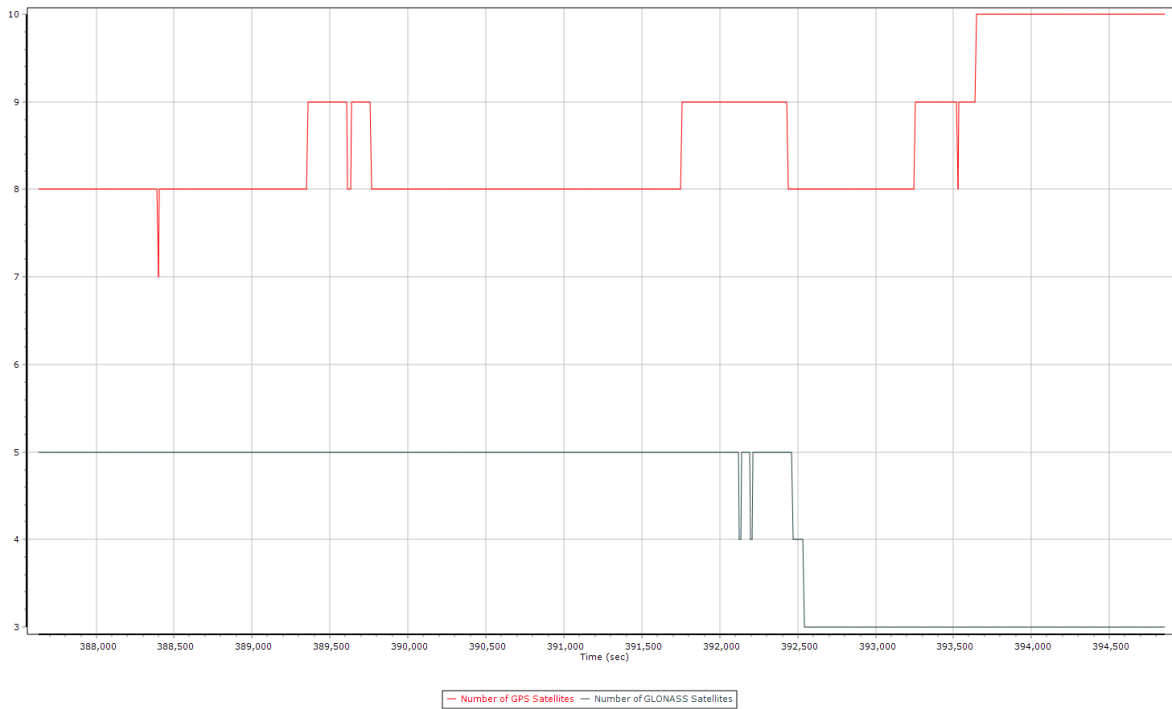
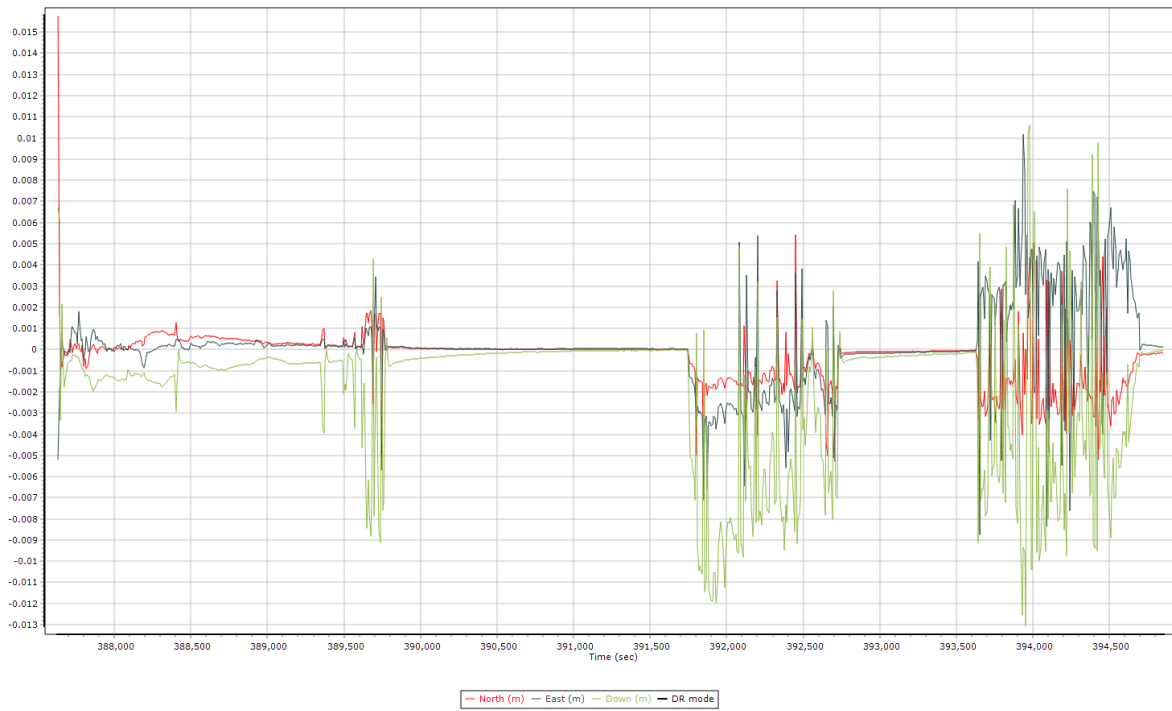
UTC Offset: 18.000

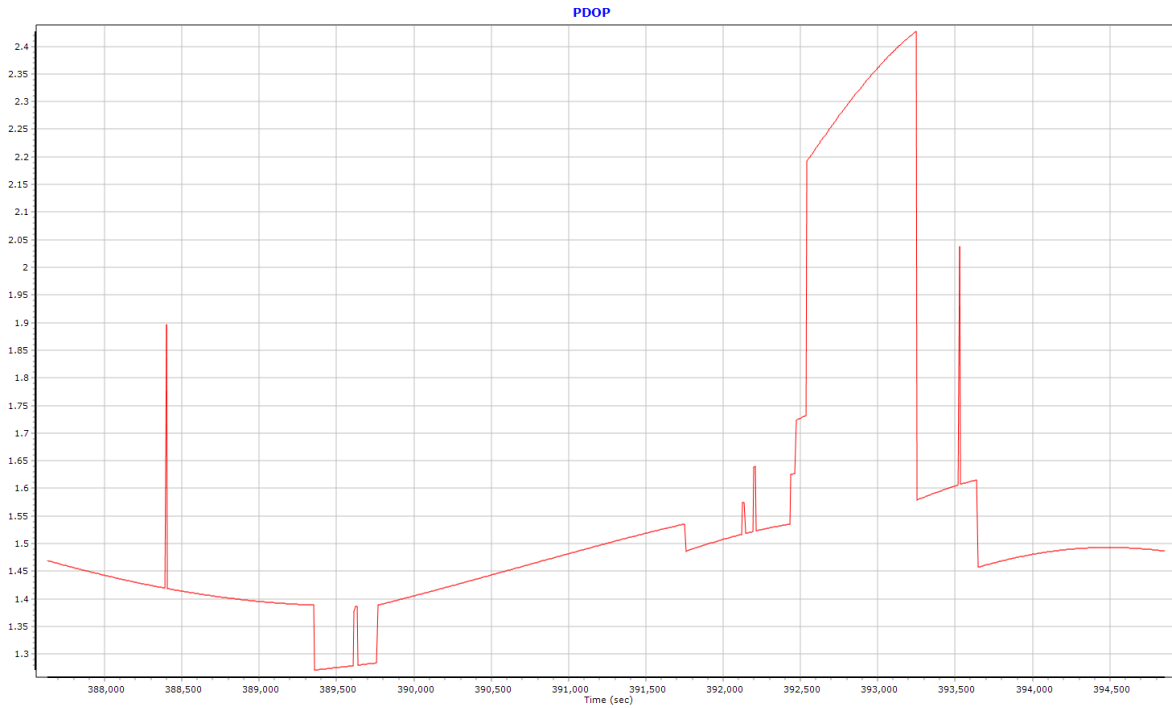
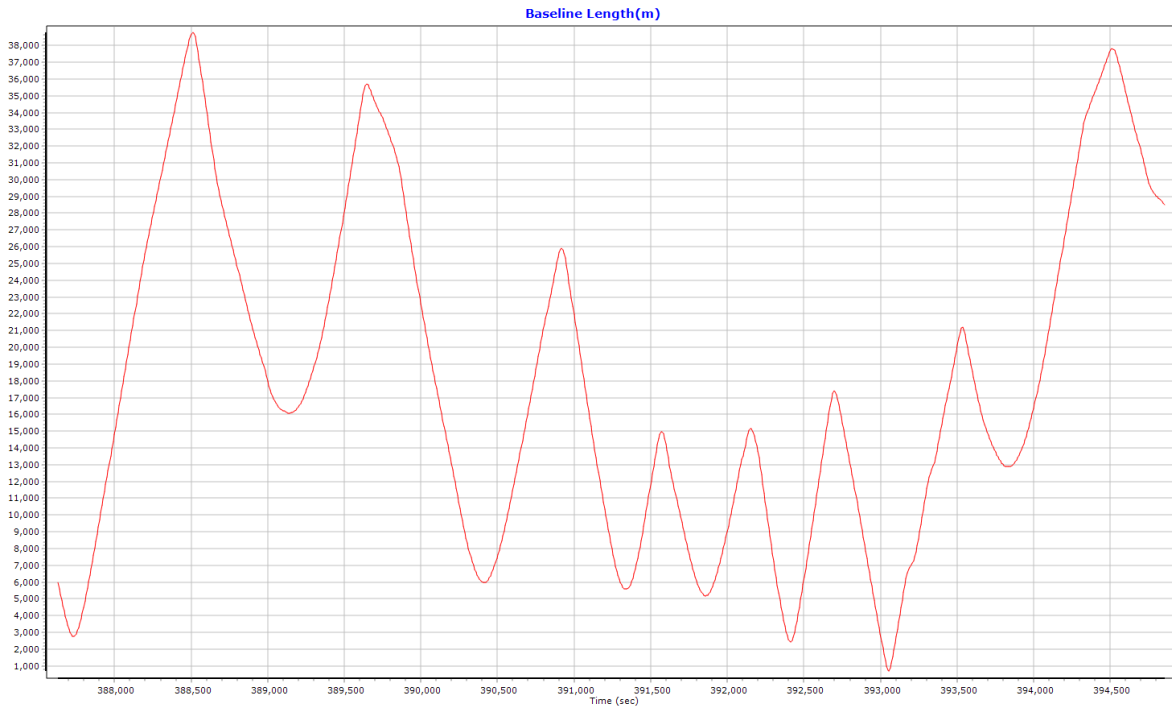
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

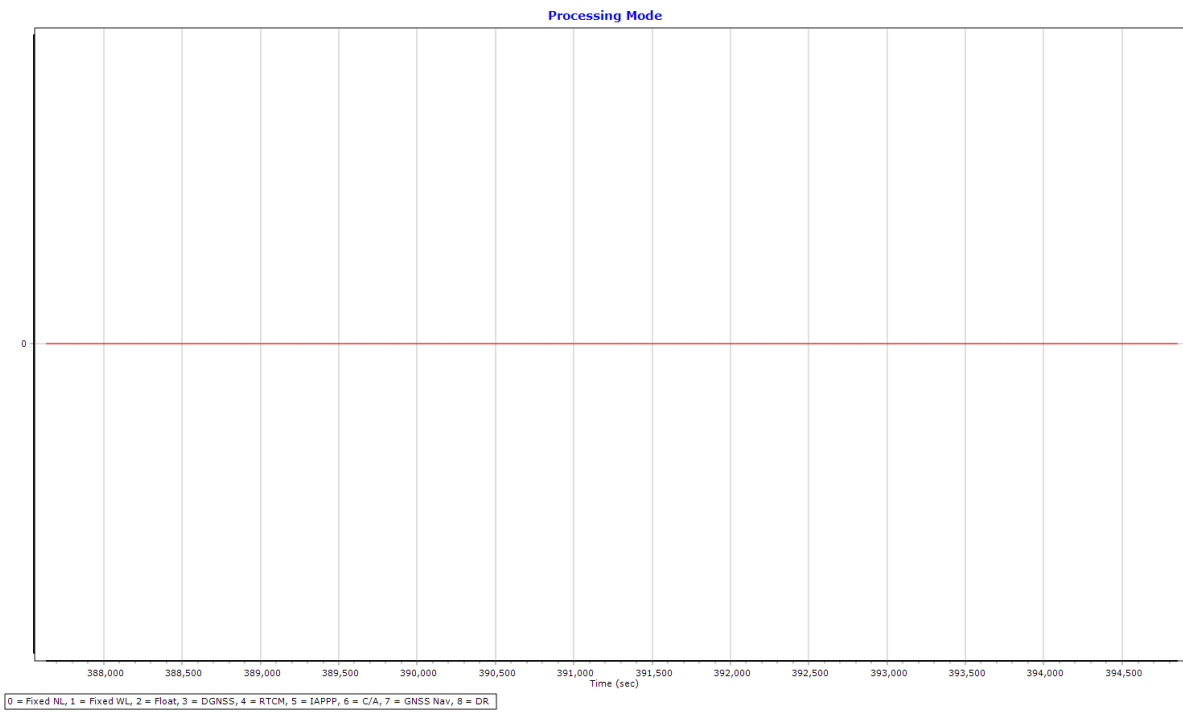
OK Cancel



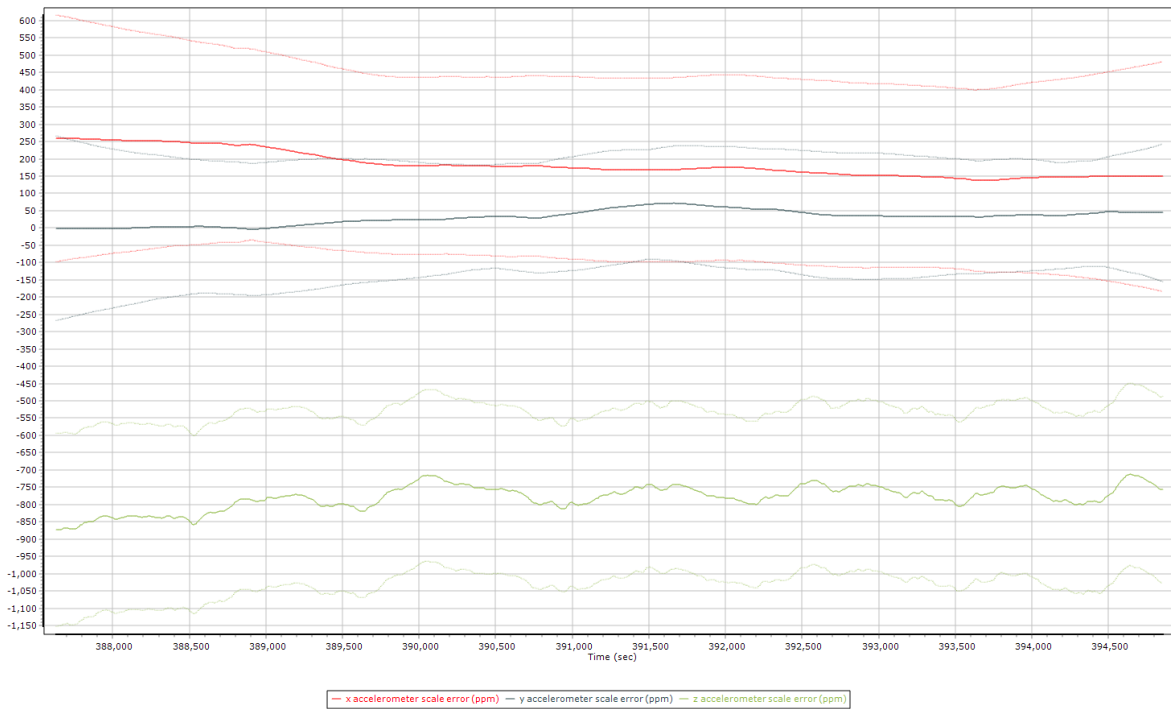
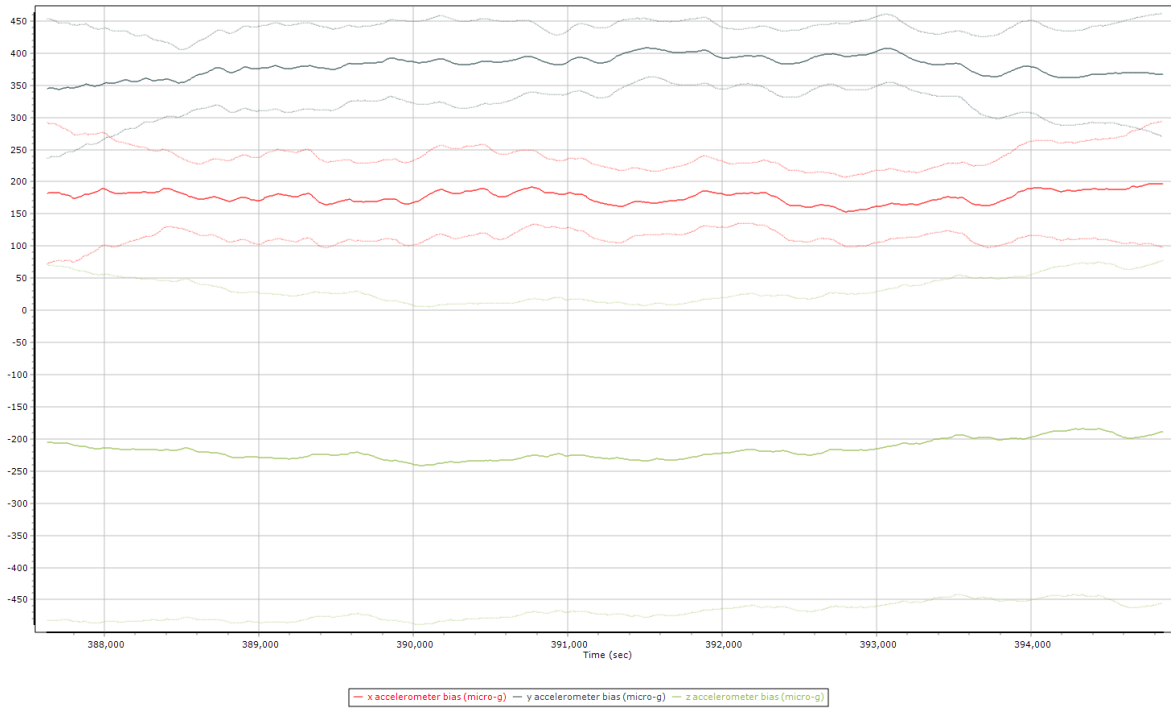


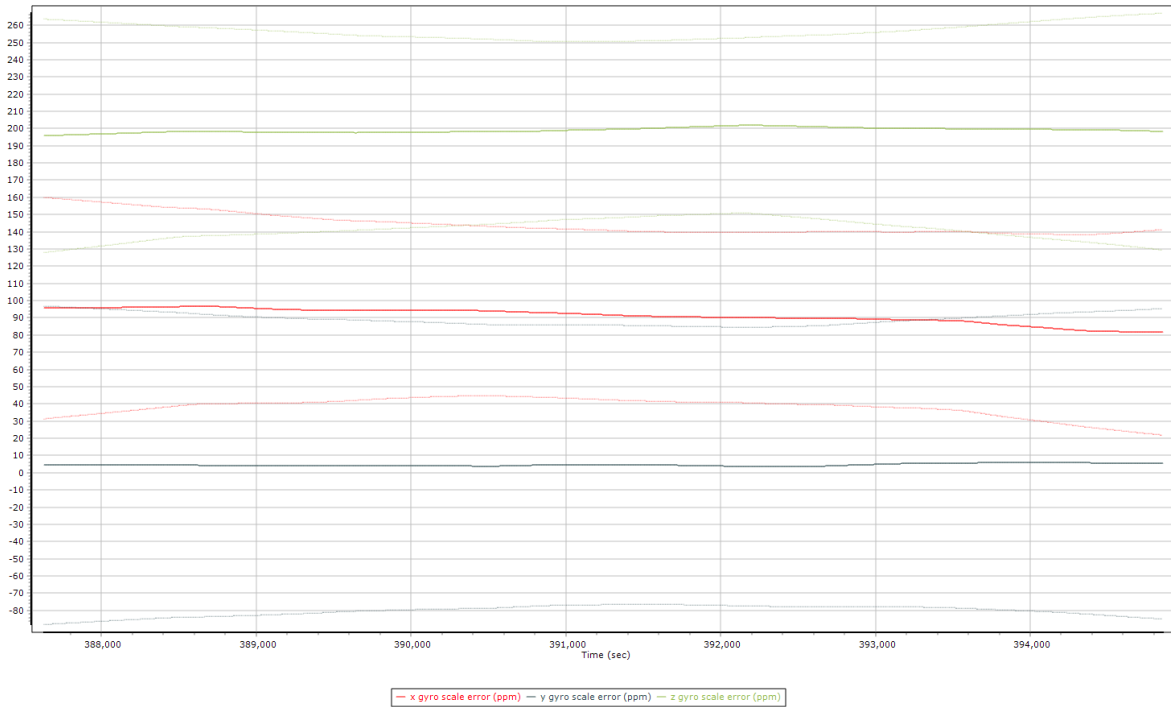
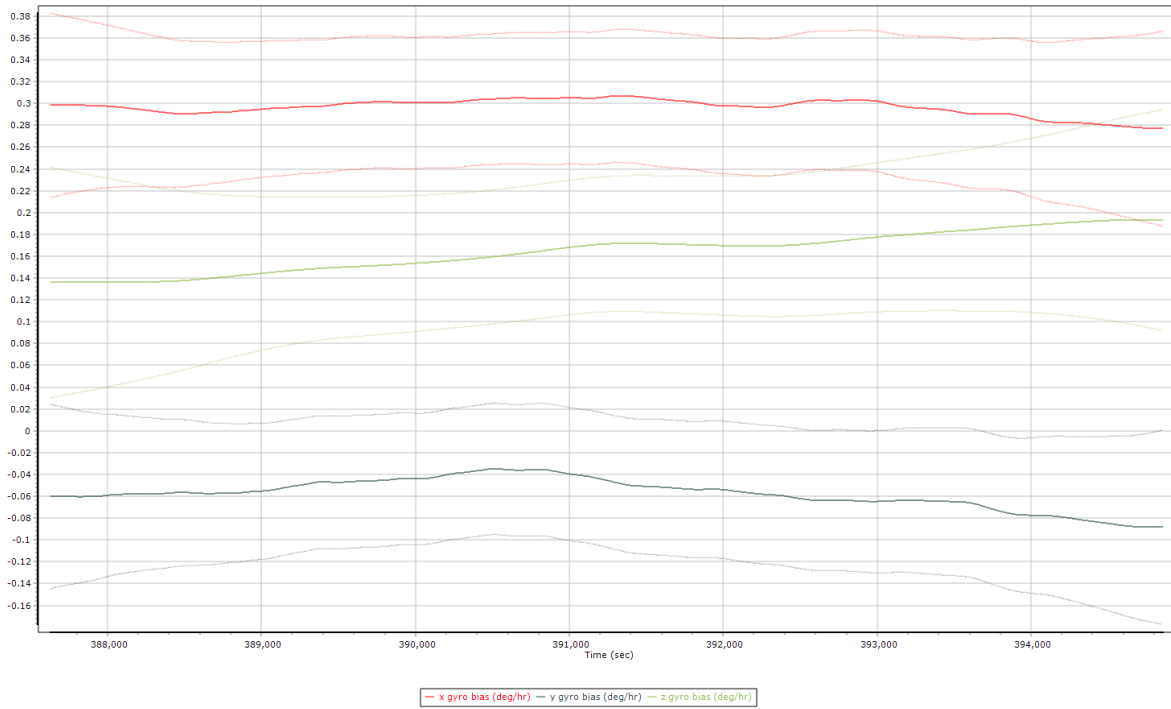




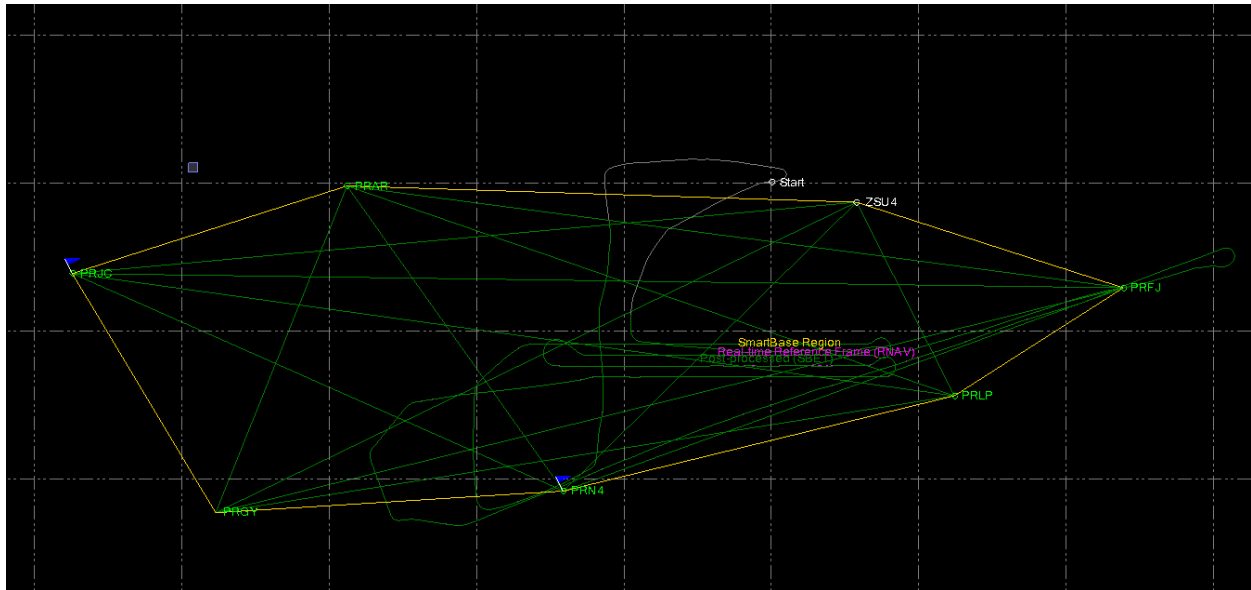


Sensor Errors





RBV19088A



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: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 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

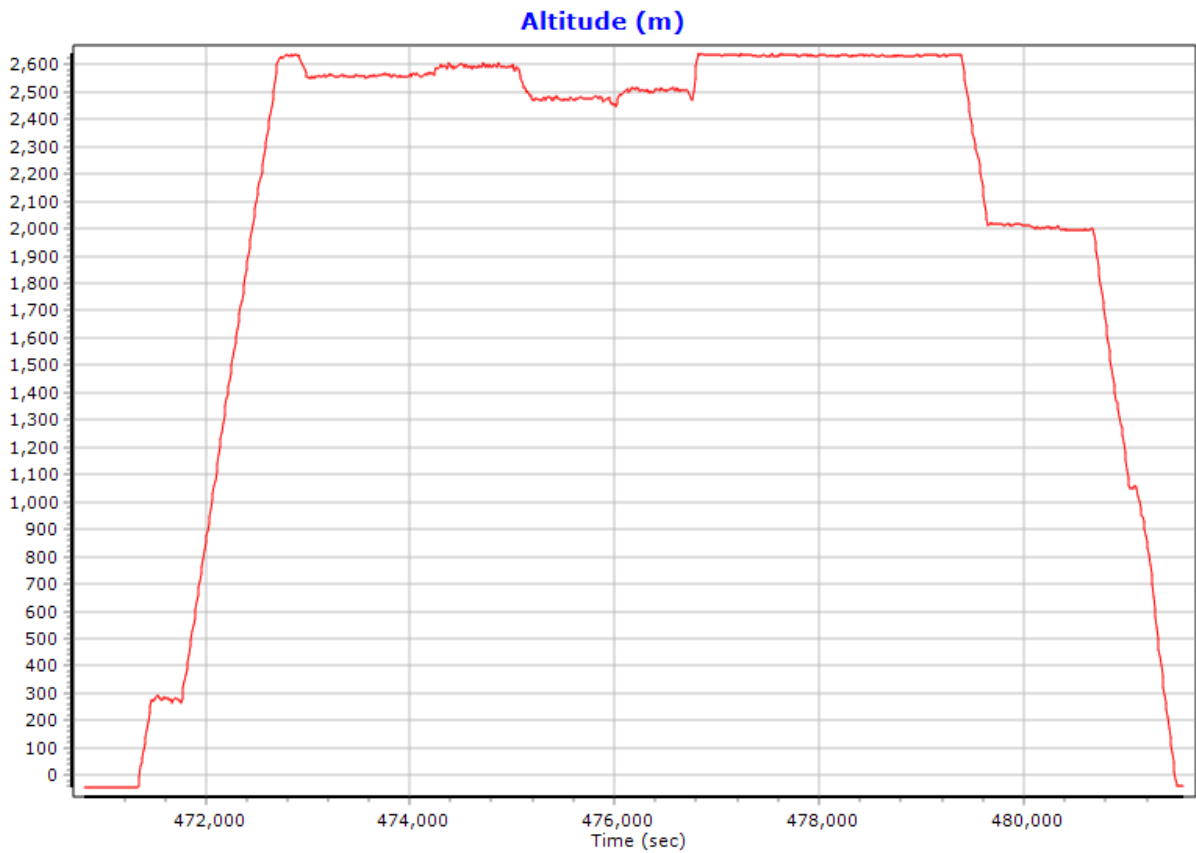
Timing

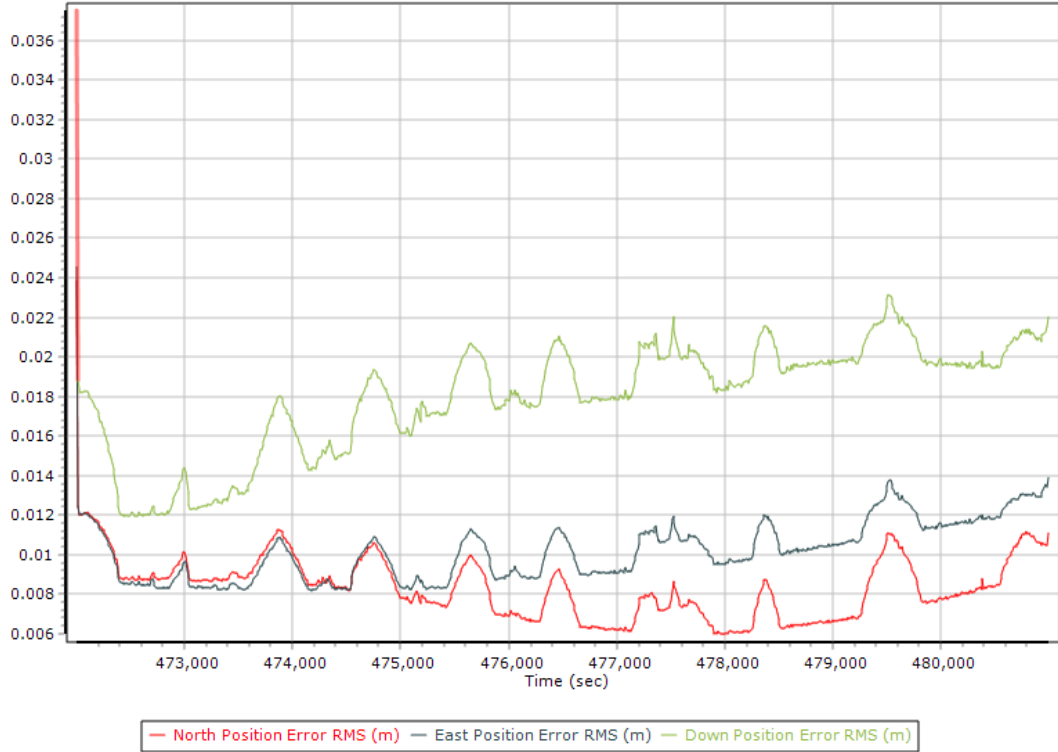
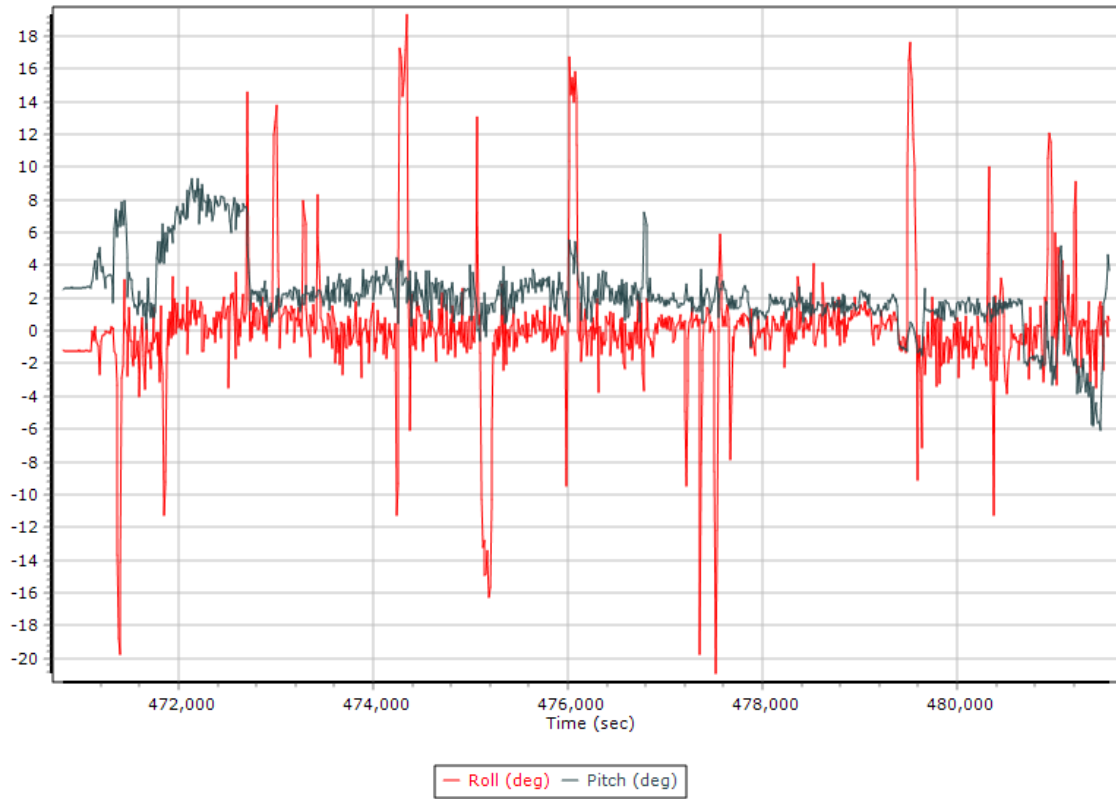
Start: 472000.000
End: 481000.000

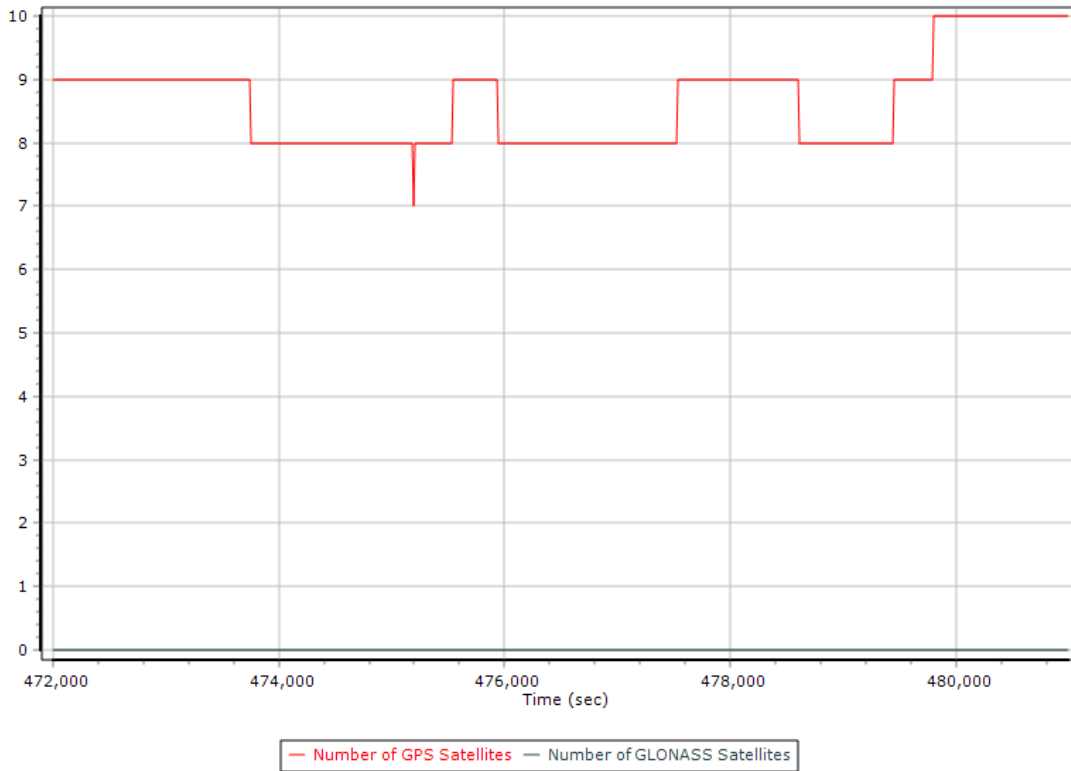
Entire time interval
 Seconds of start week

UTC Offset: 18.000

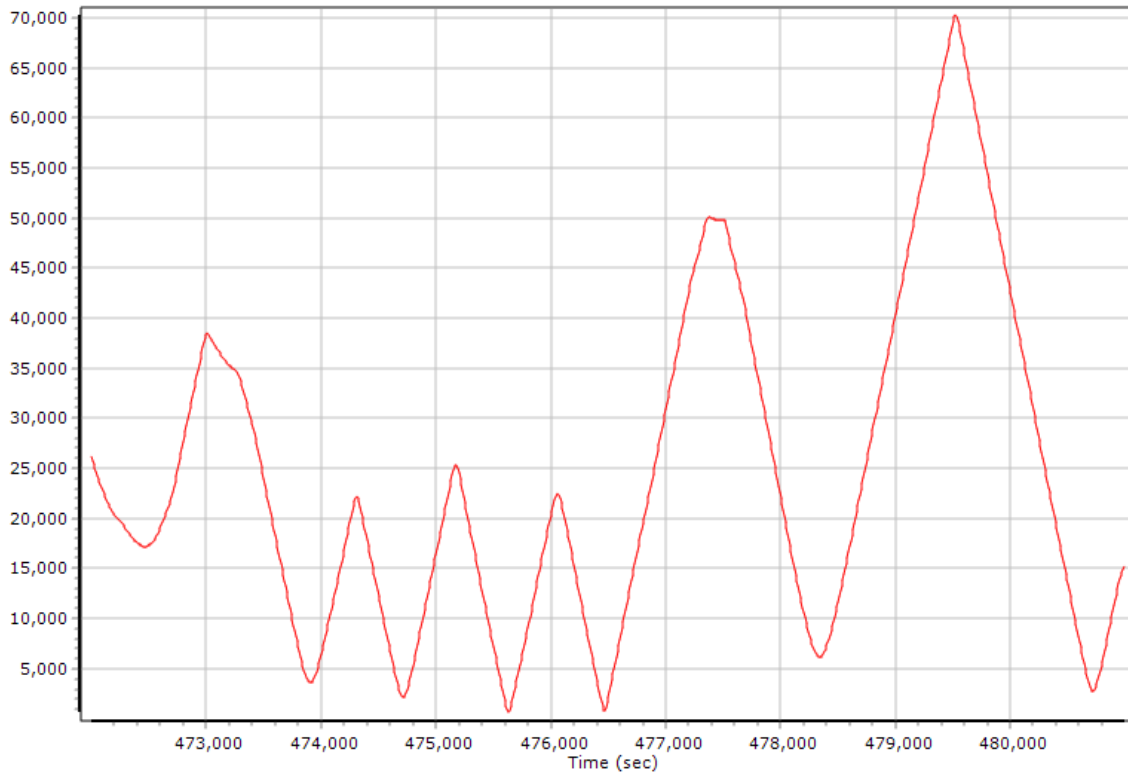
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000



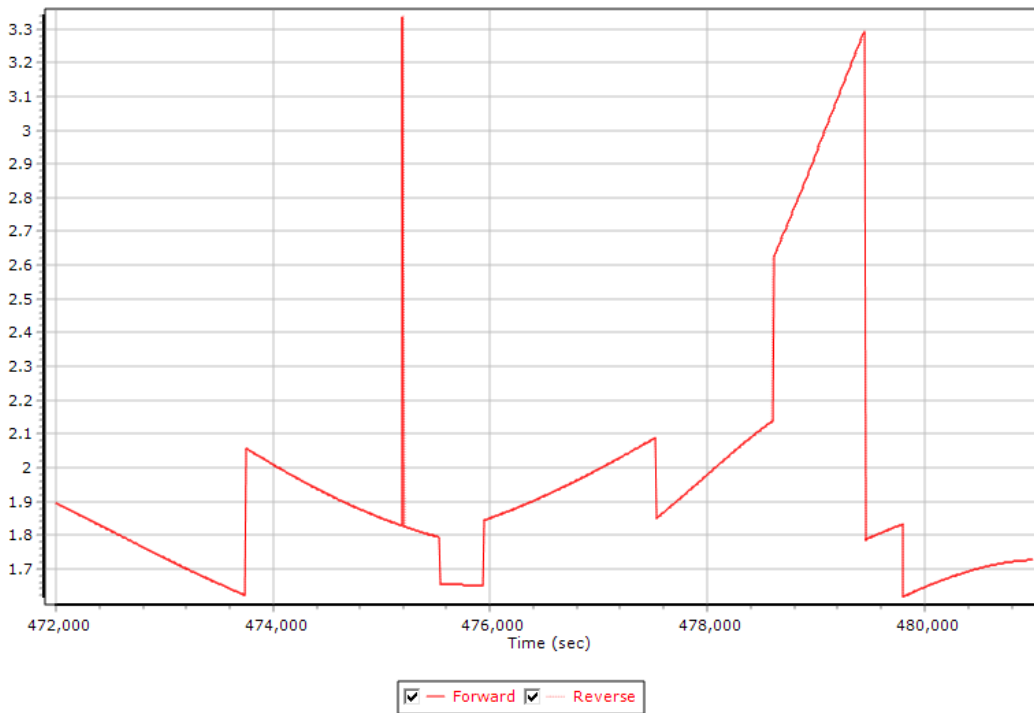




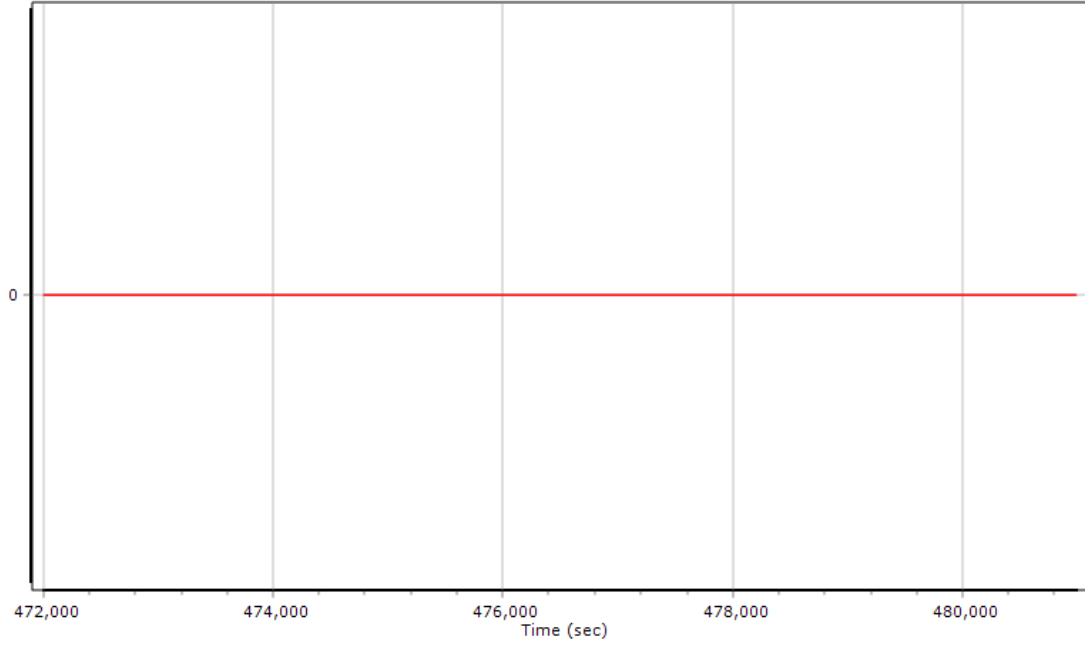
Baseline Length(m)



PDOP



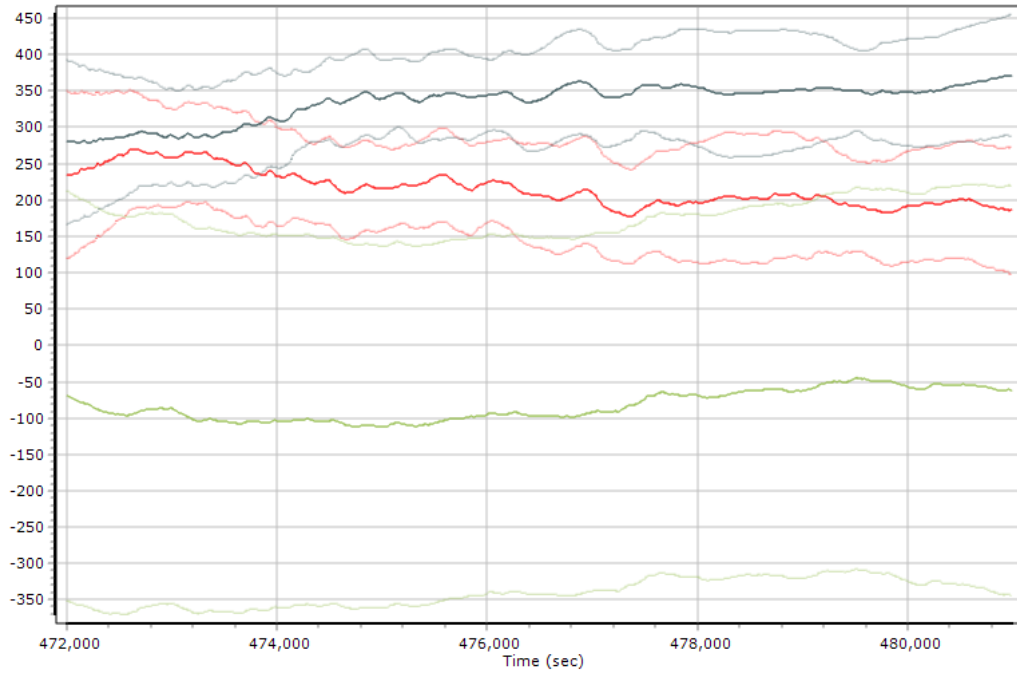
Processing Mode



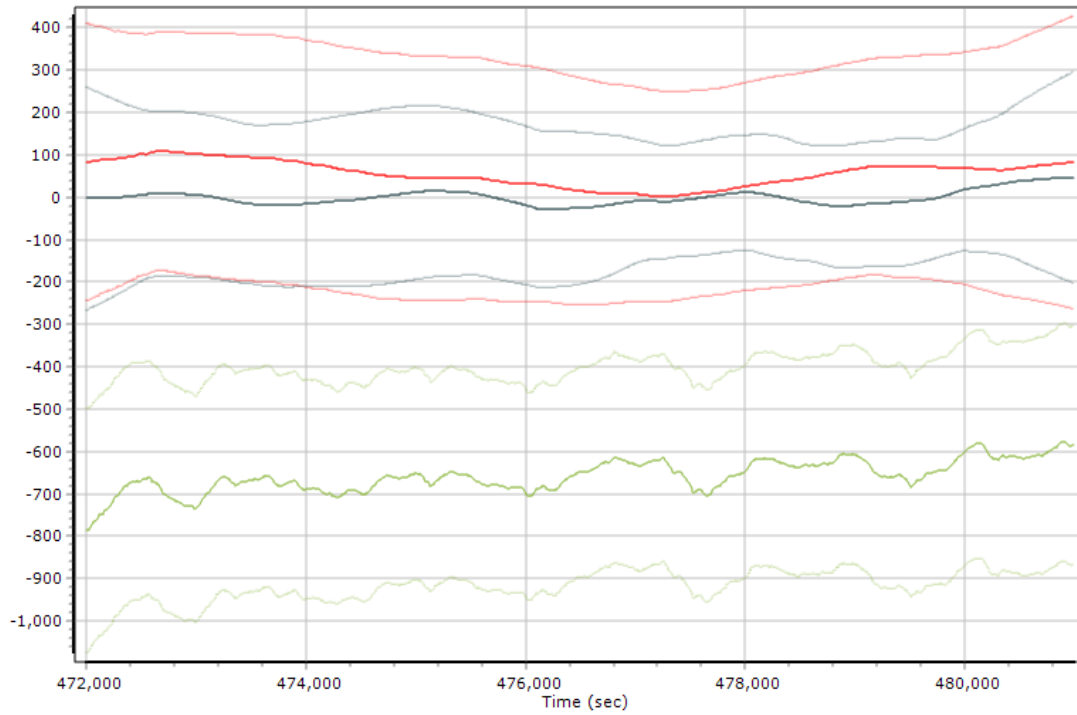
— Forward — Reverse

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

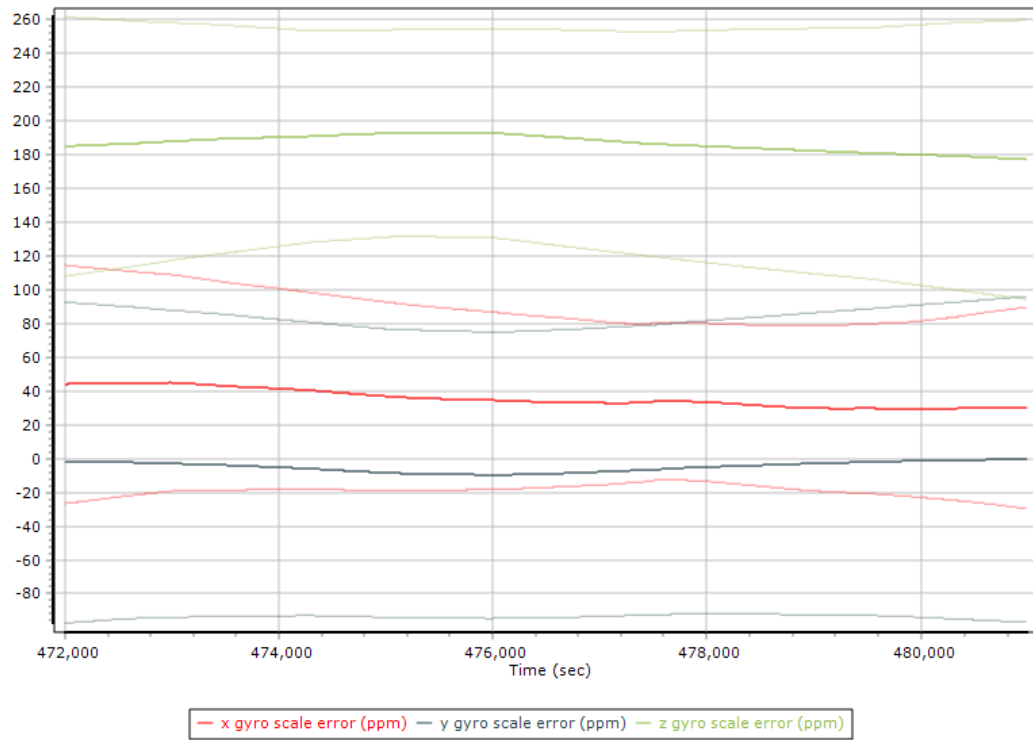
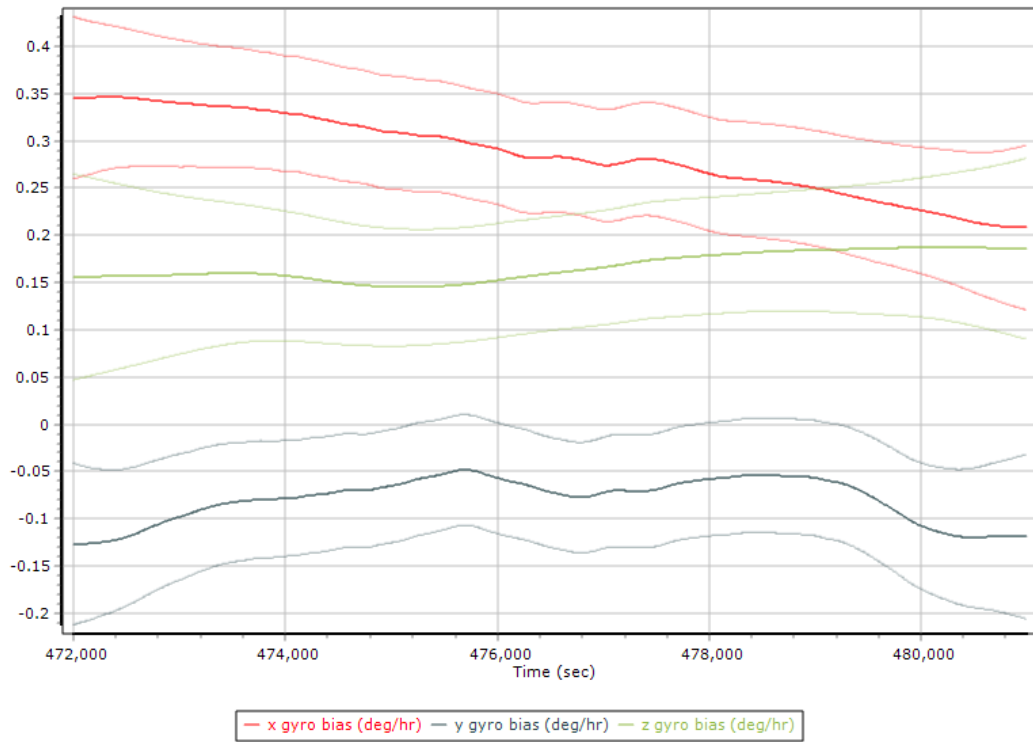
Sensor Errors



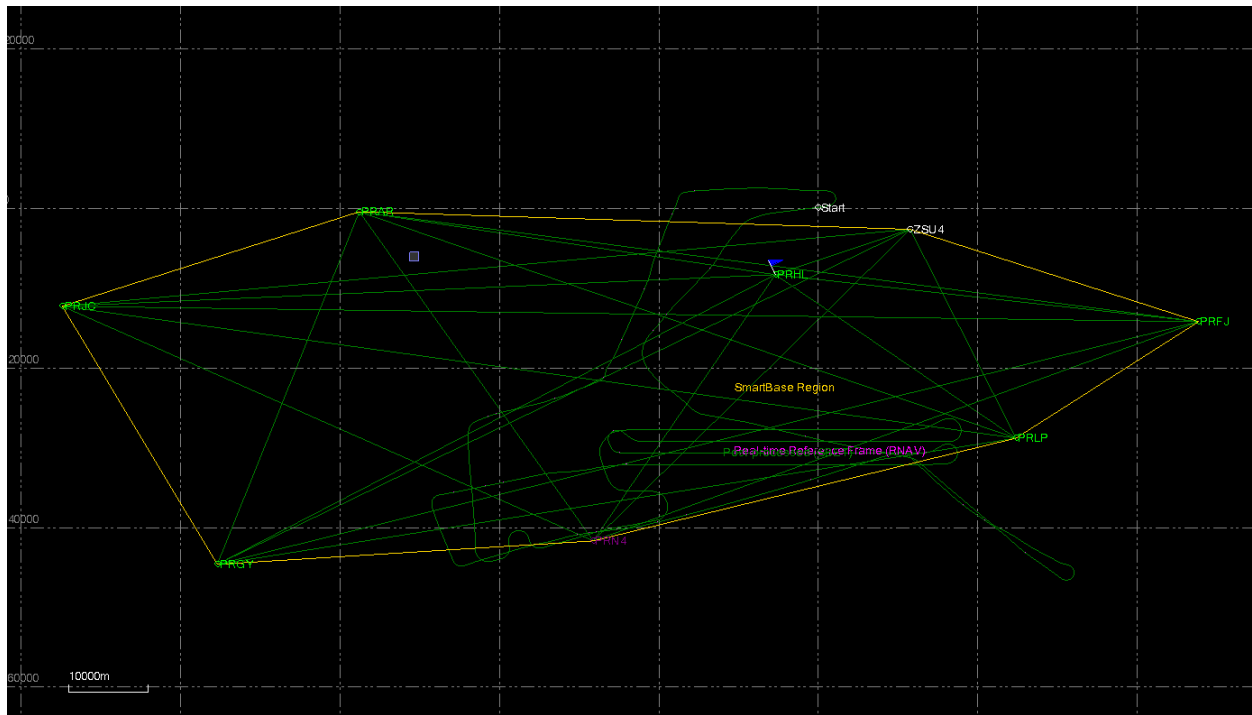
x accelerometer bias (micro-g) y accelerometer bias (micro-g) z accelerometer bias (micro-g)



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



RBV19090A



Project Settings [X]

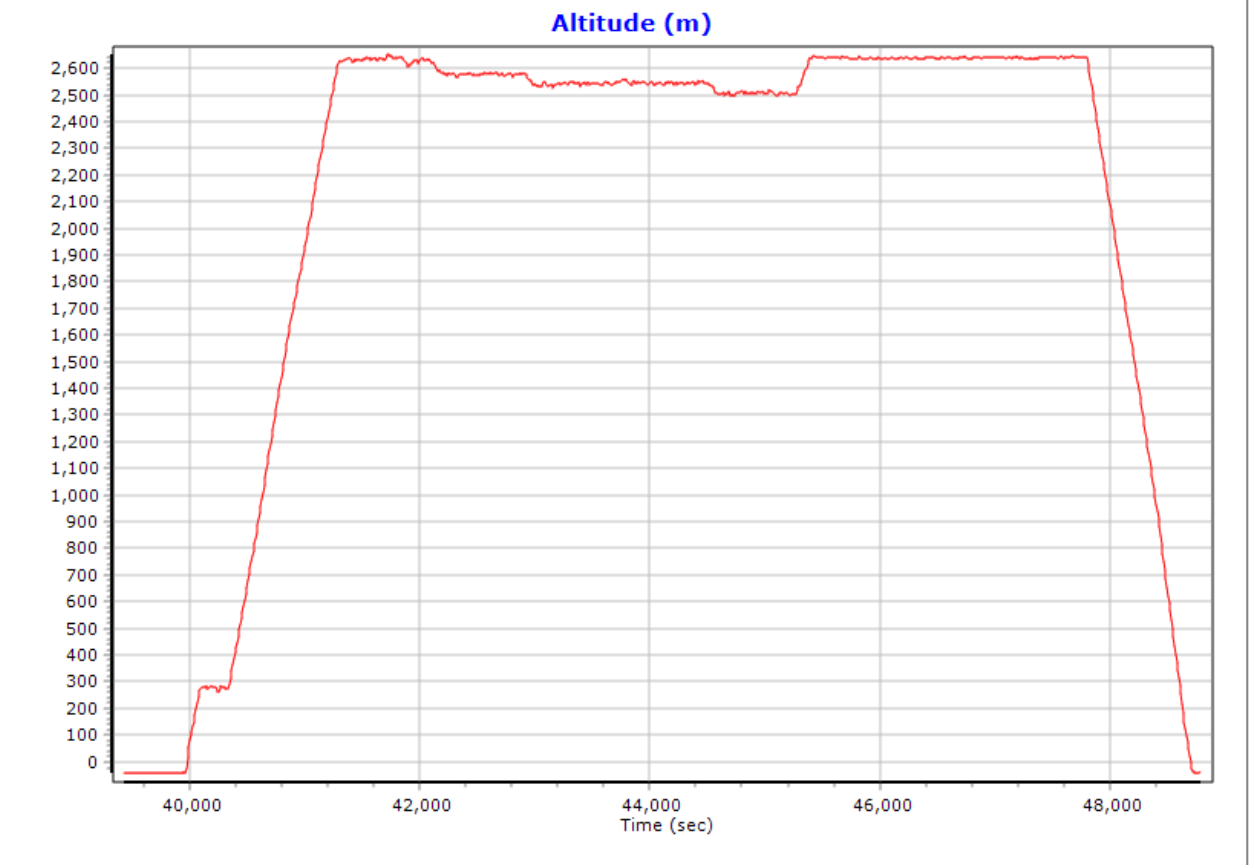
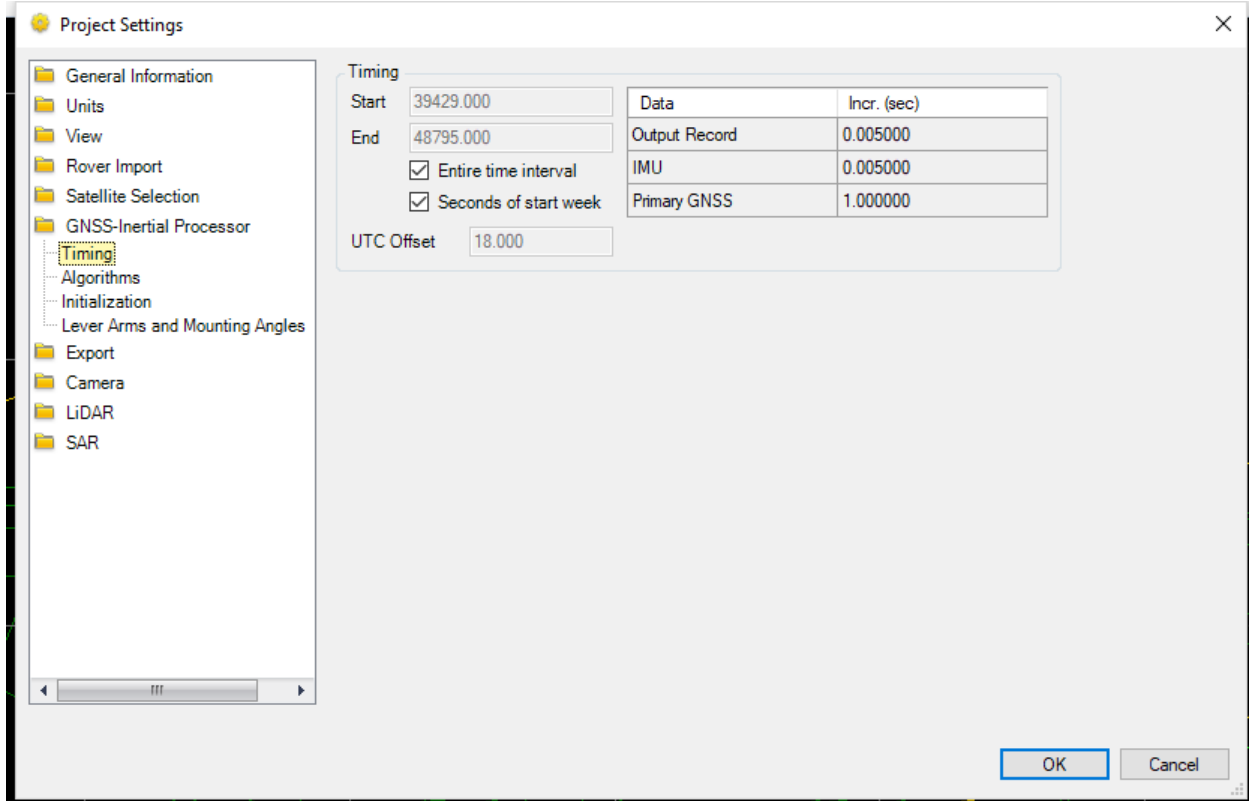
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

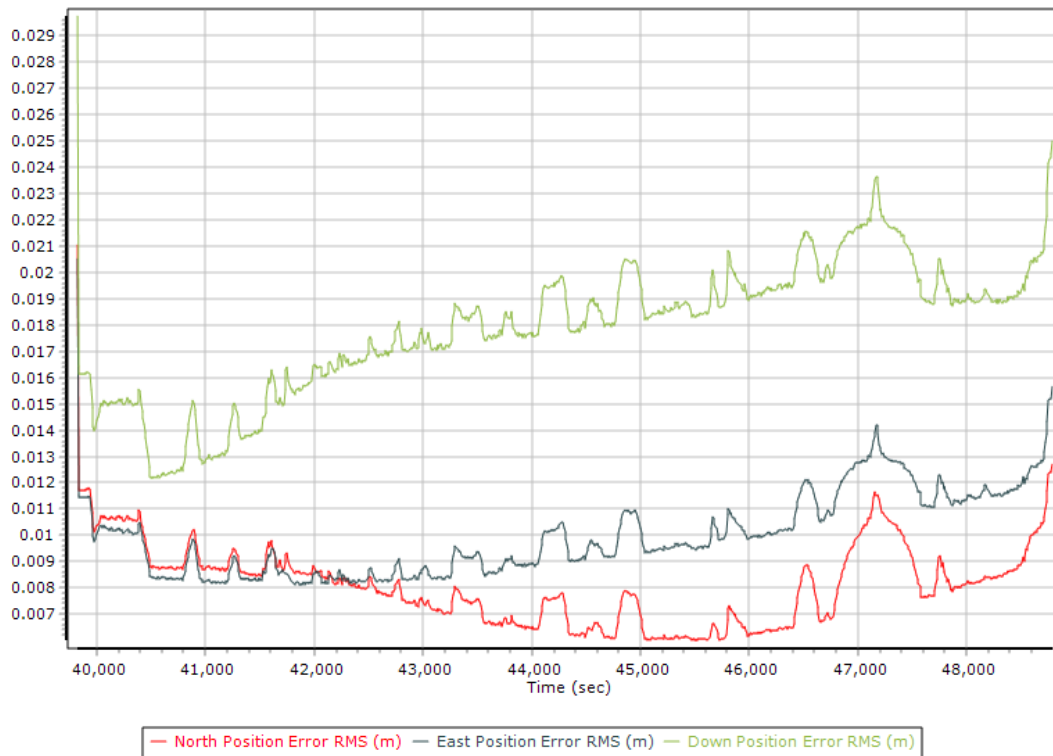
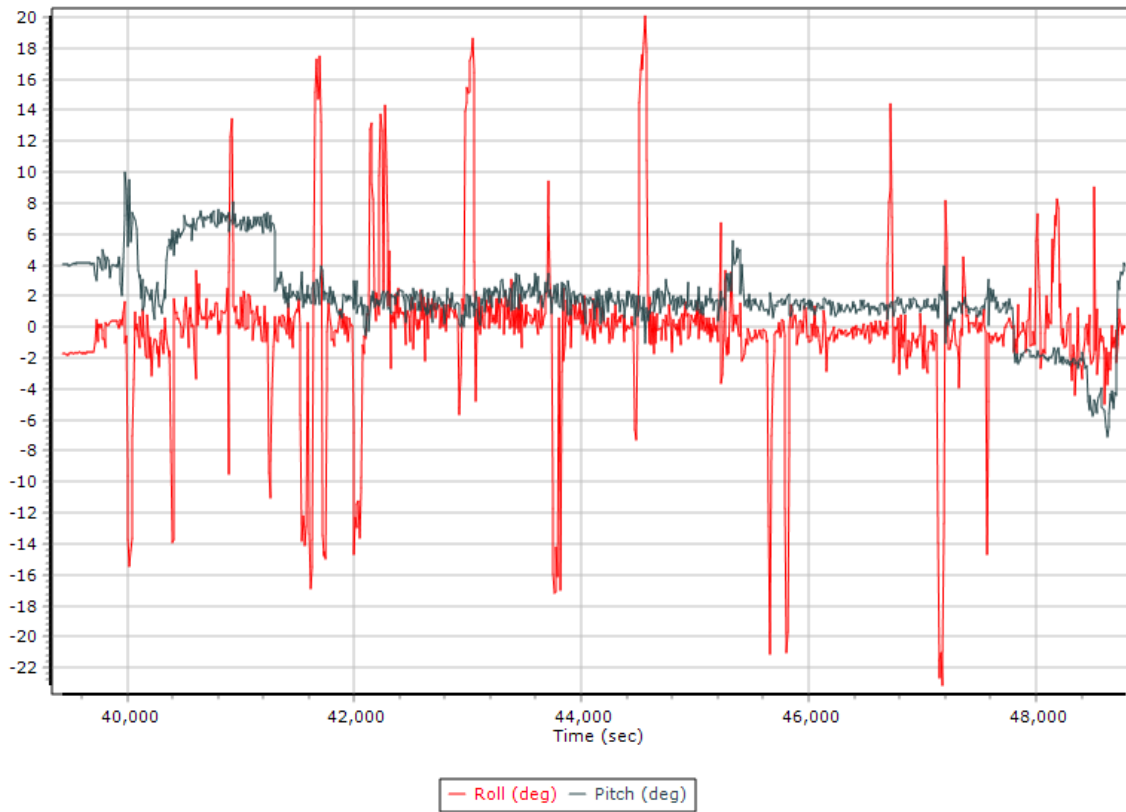
Reference to IMU Lever Arm	Reference to IMU Mounting Angles
X: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 m	Z: 0.000 deg

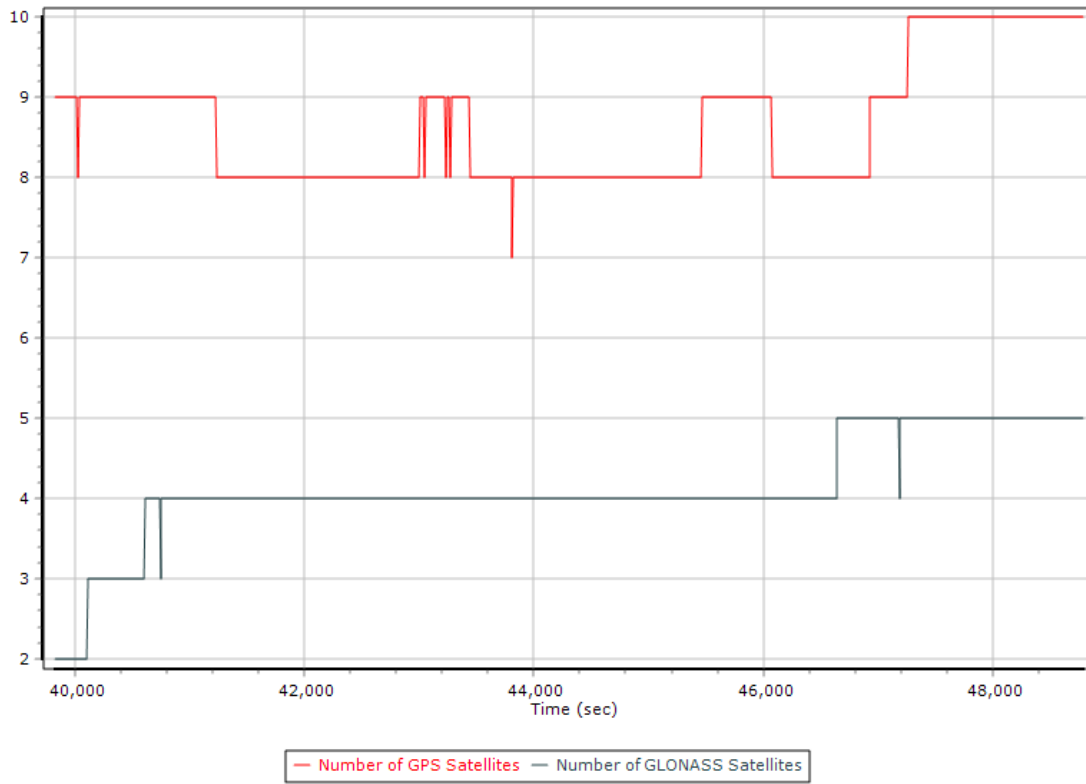
Standard Deviation: [Slider] <3cm 10cm 50cm 1m 10m

[OK] [Cancel]

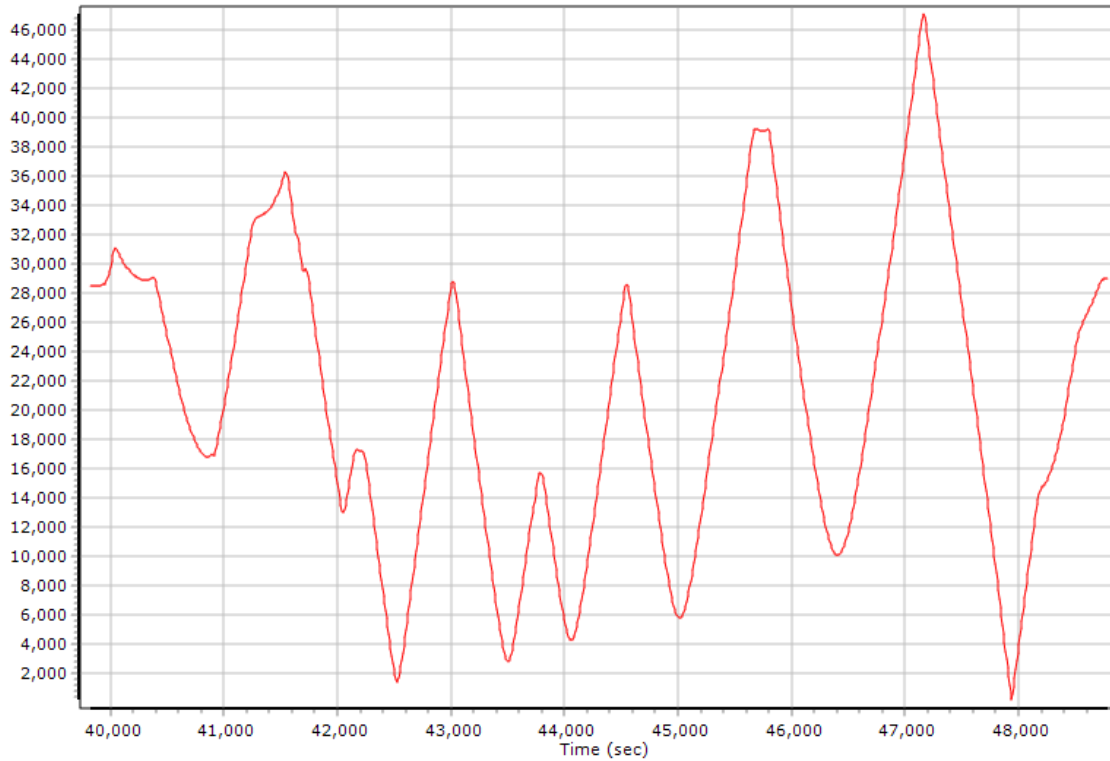


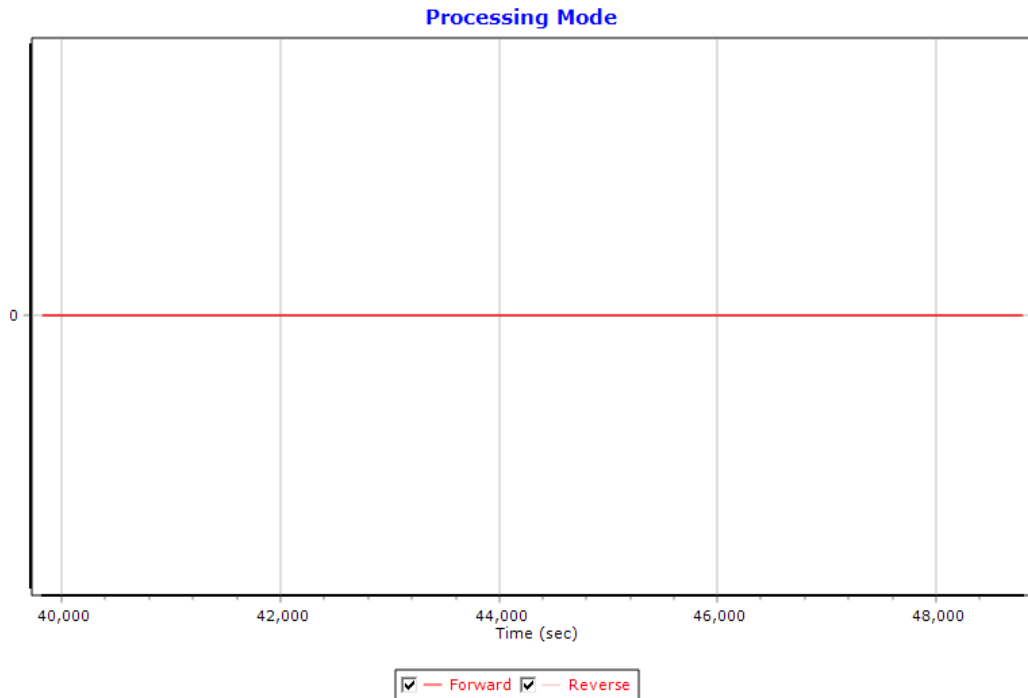
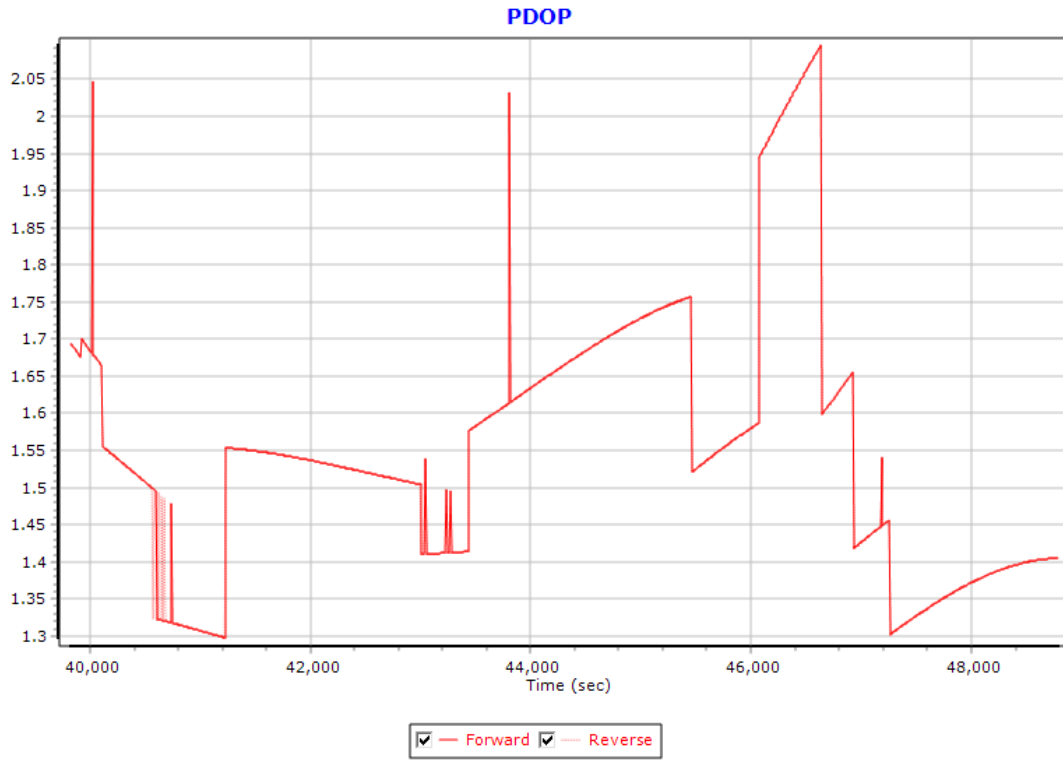






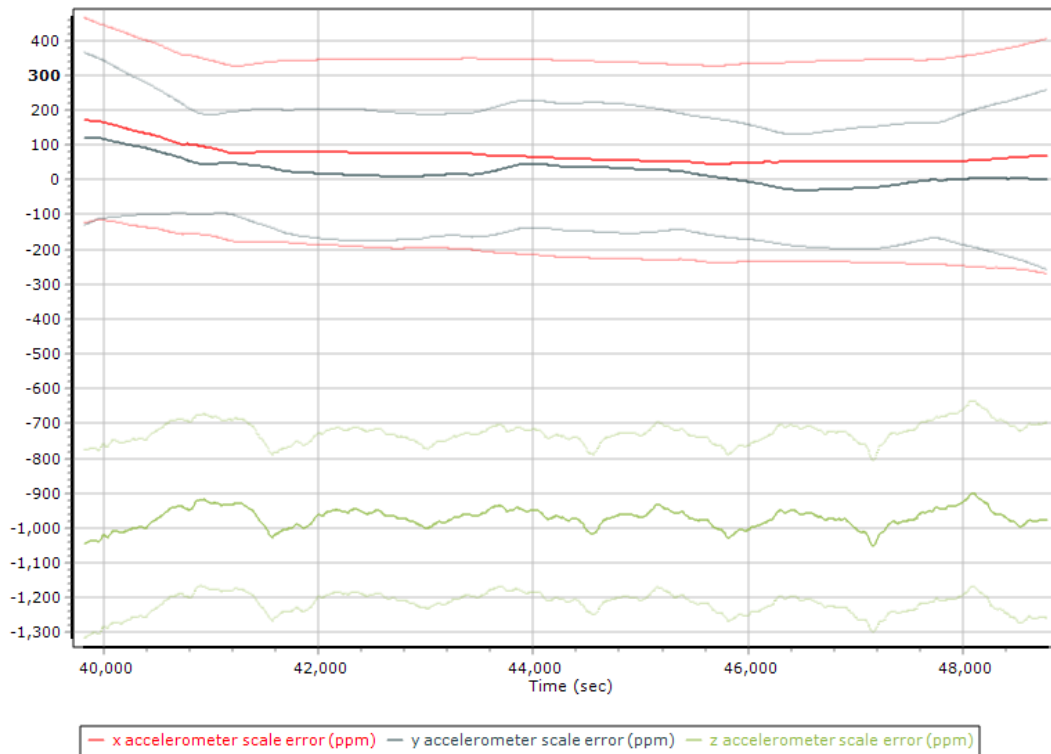
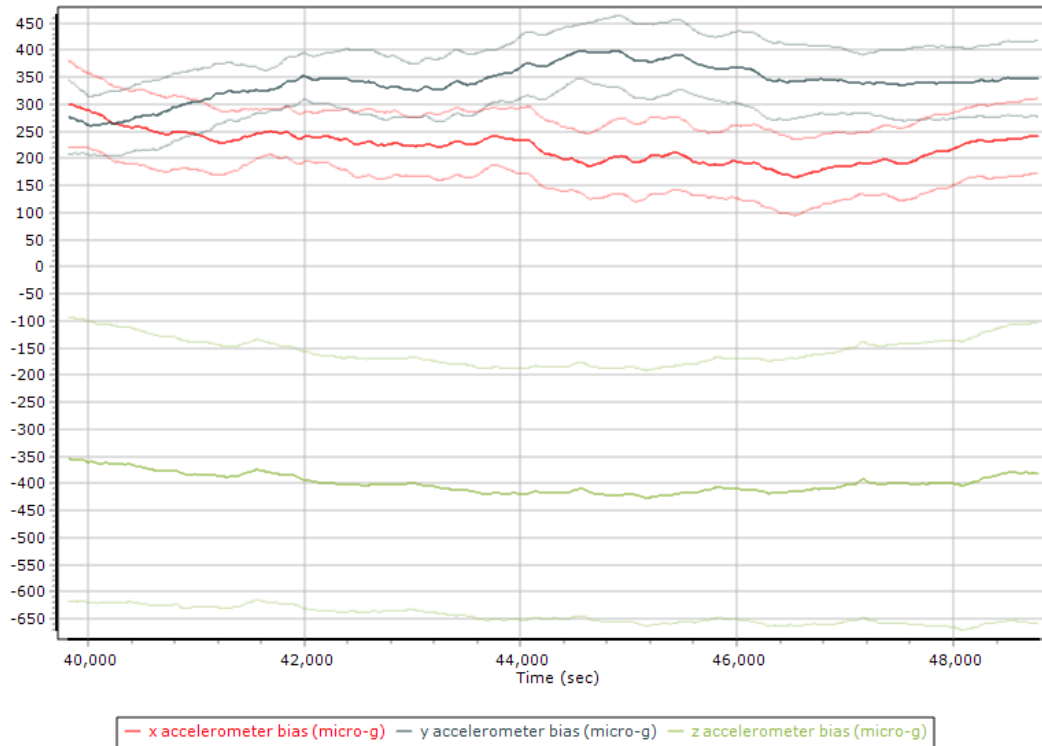
Baseline Length(m)

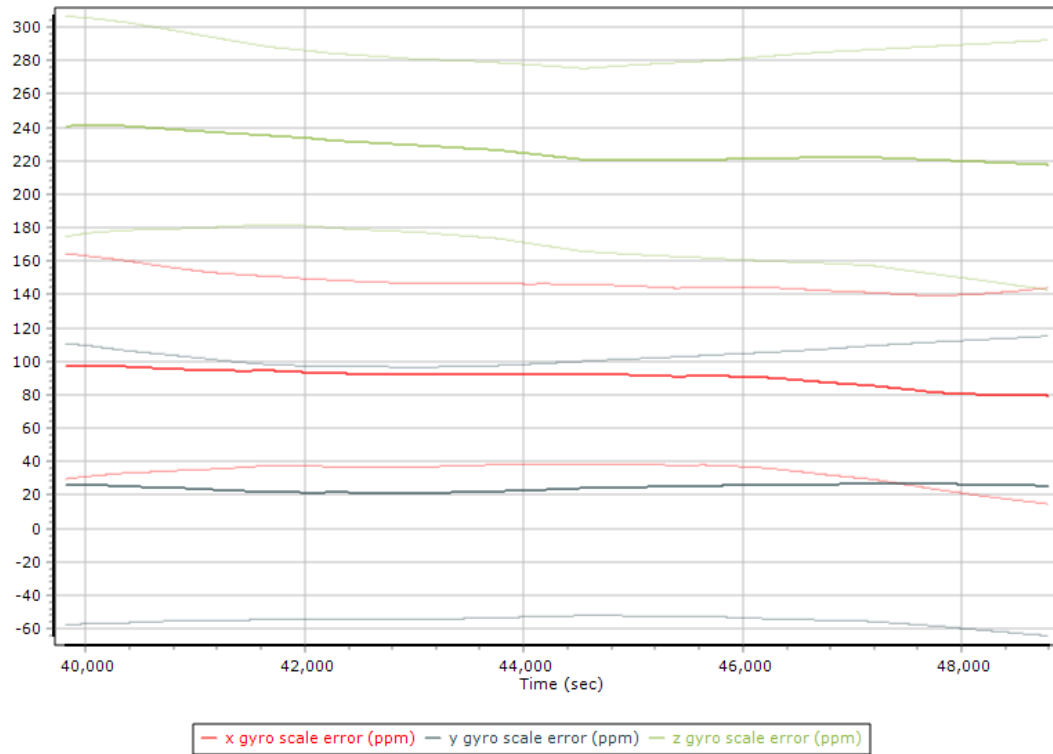
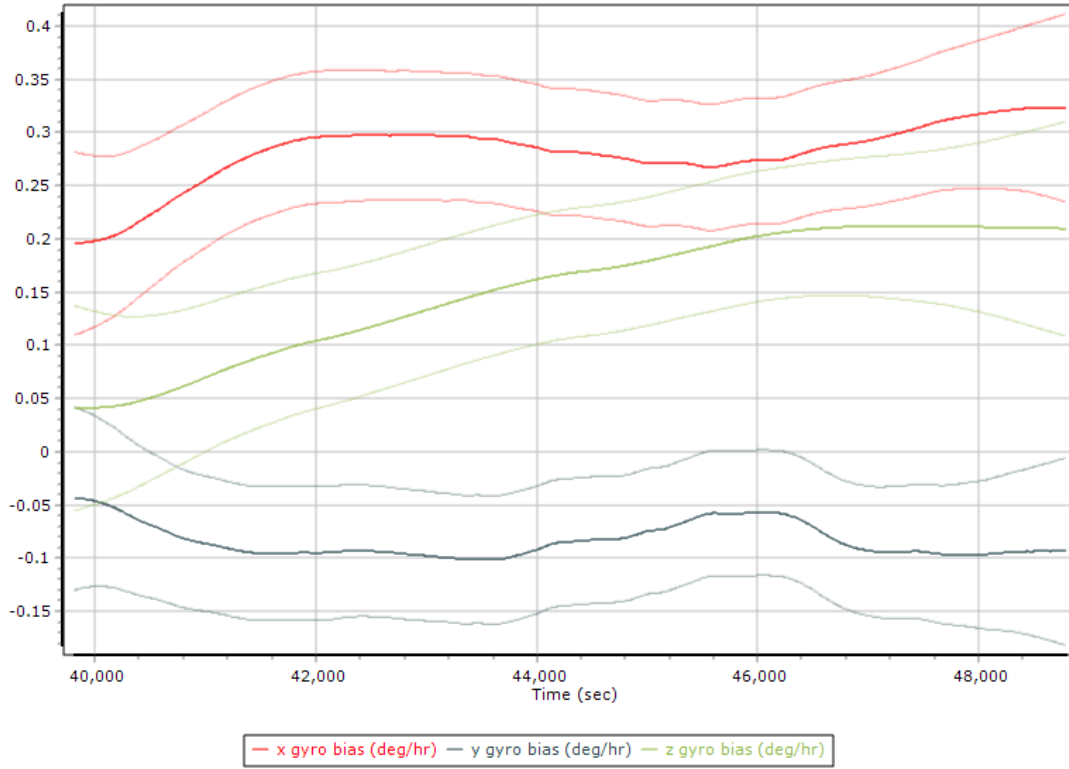




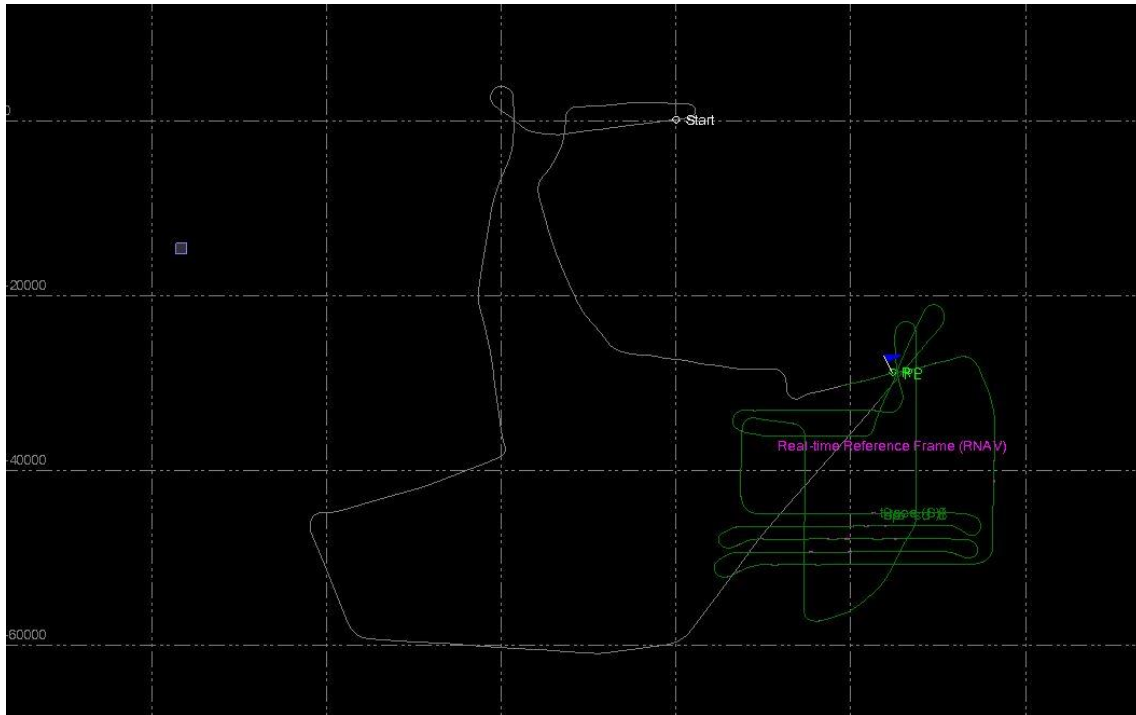
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

Sensor Errors





RBV19091A



Project Settings

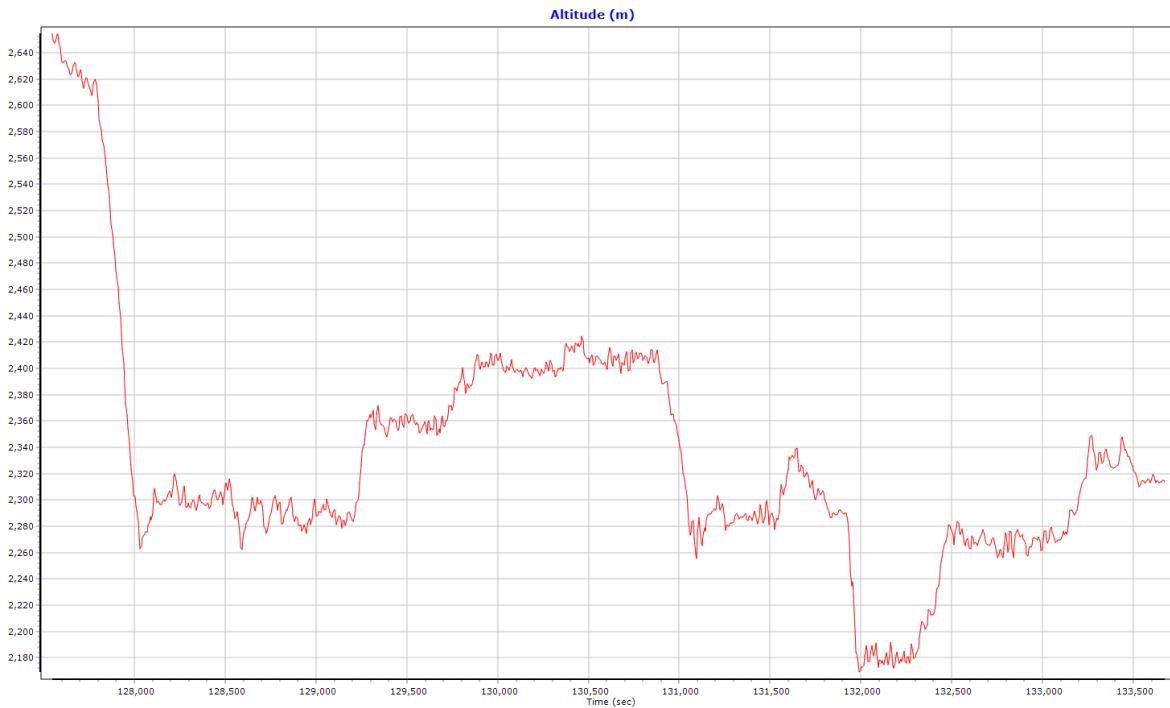
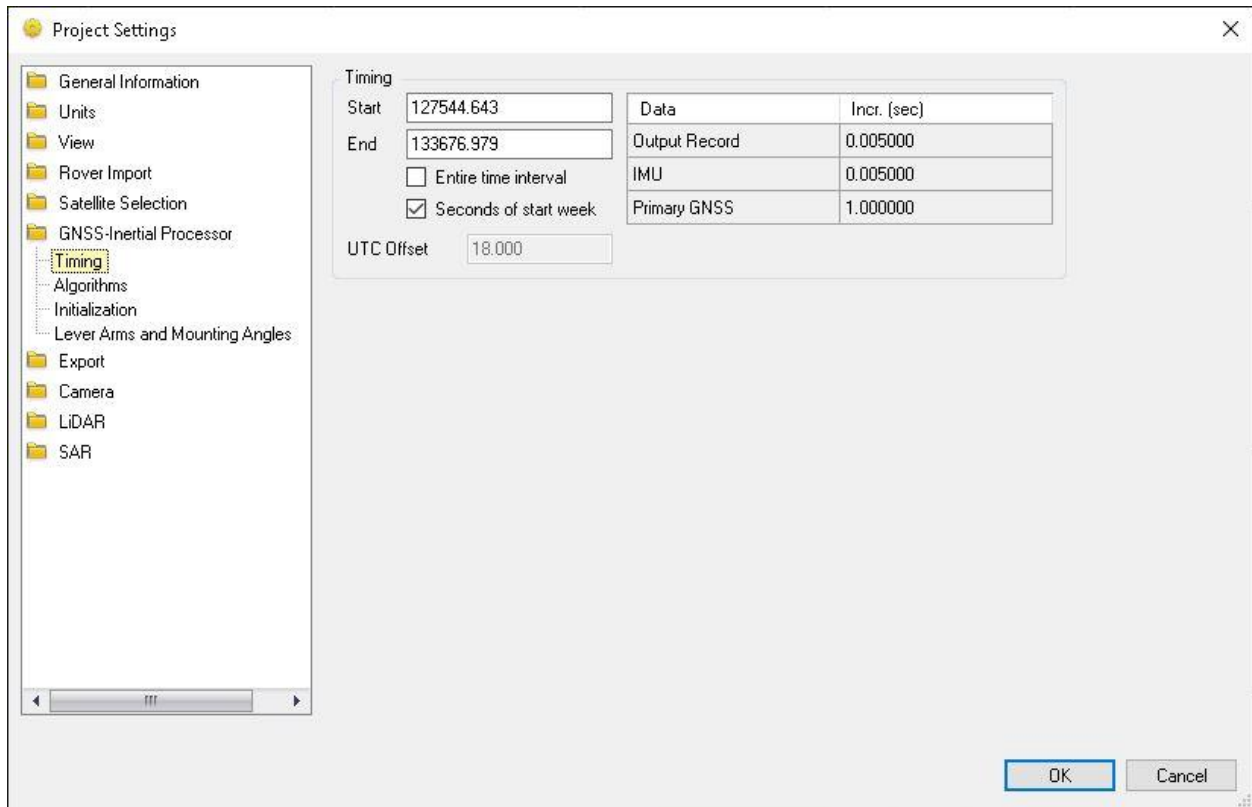
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

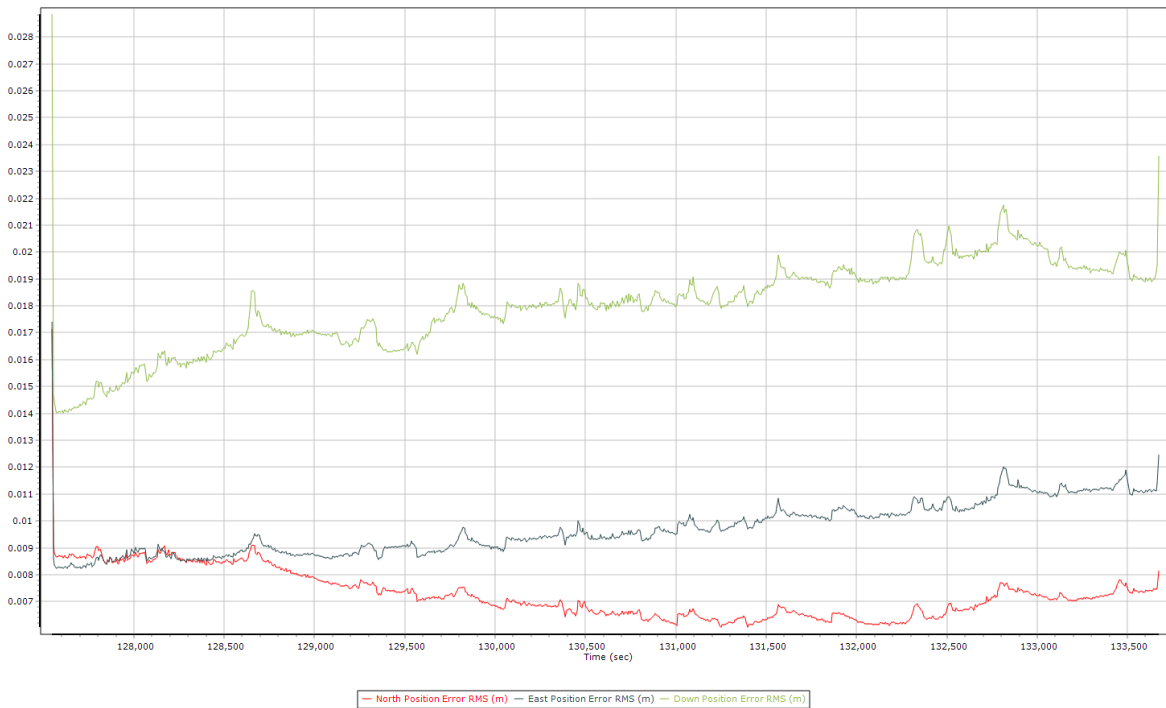
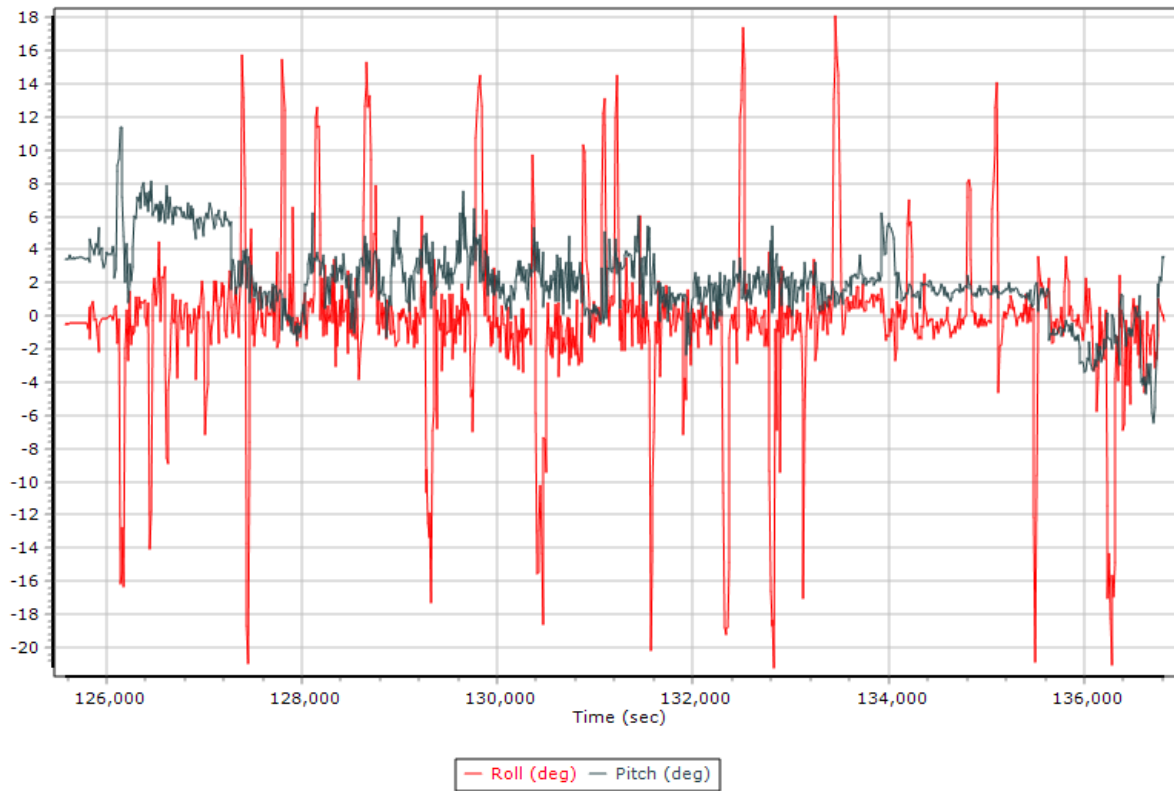
Reference to IMU Lever Arm	Reference to IMU Mounting Angles
X: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

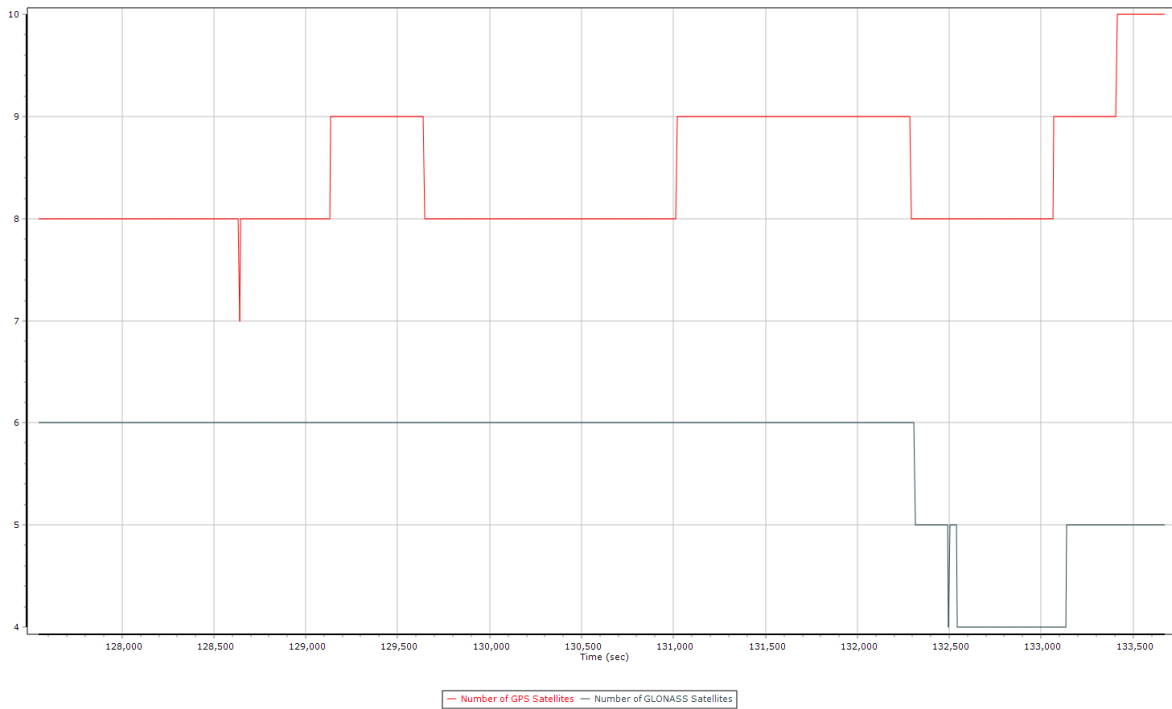
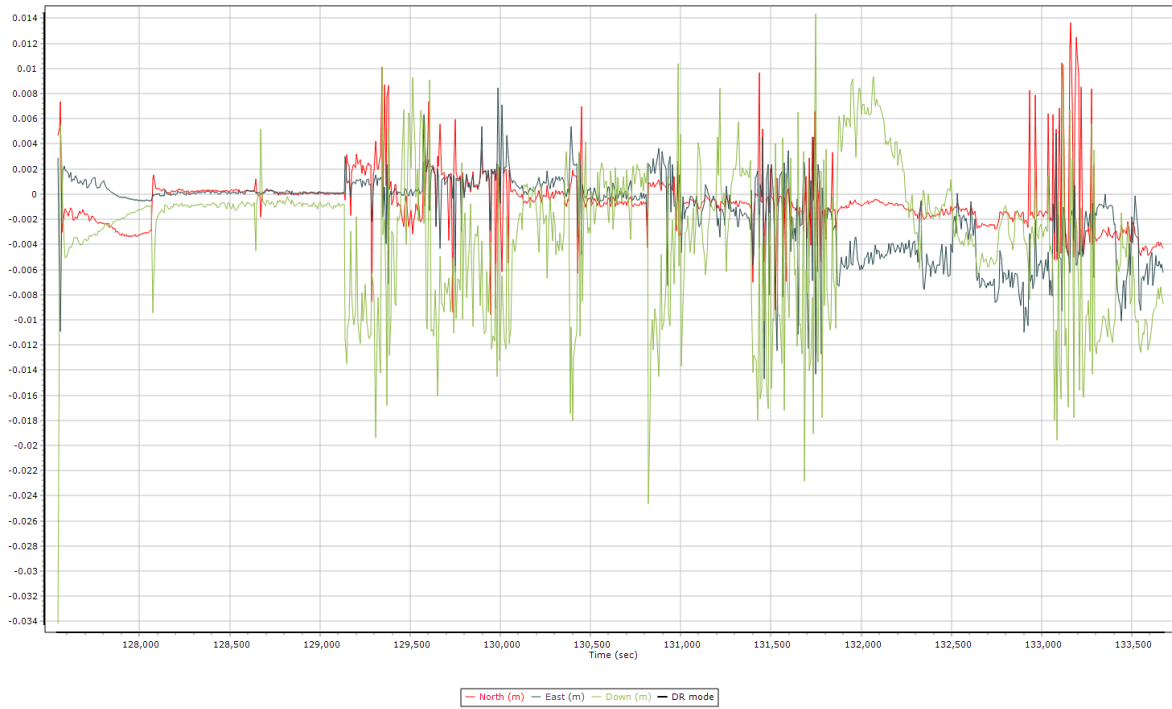
Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 m	Z: 0.000 deg

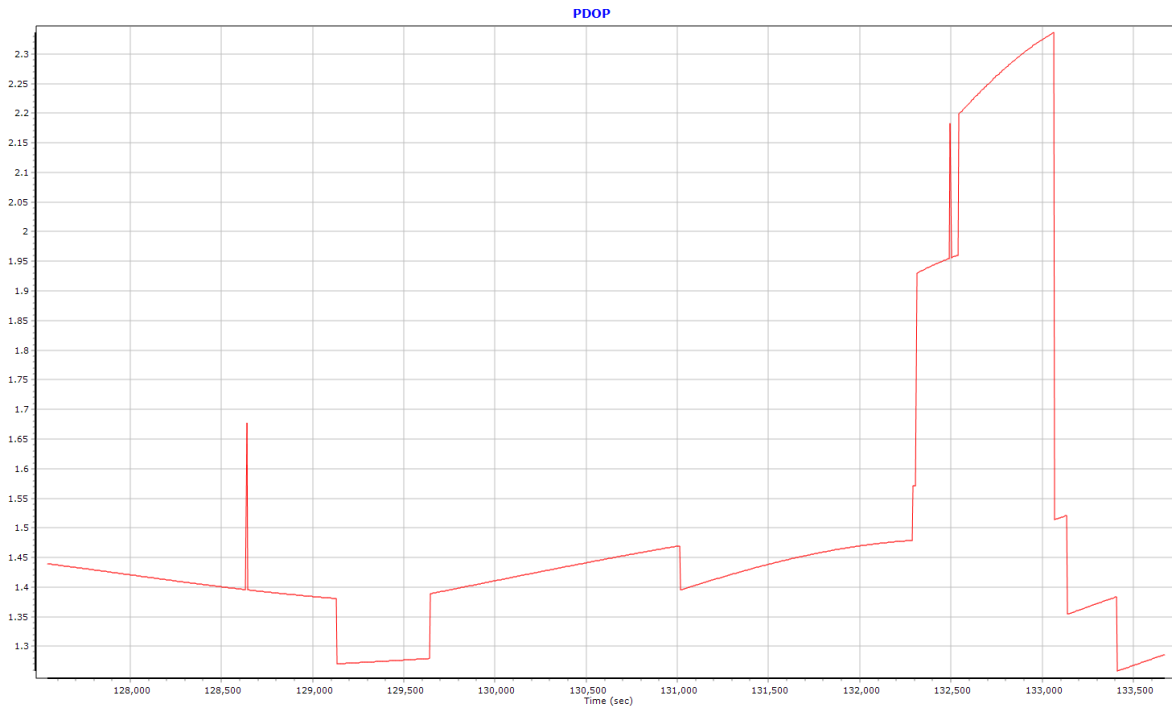
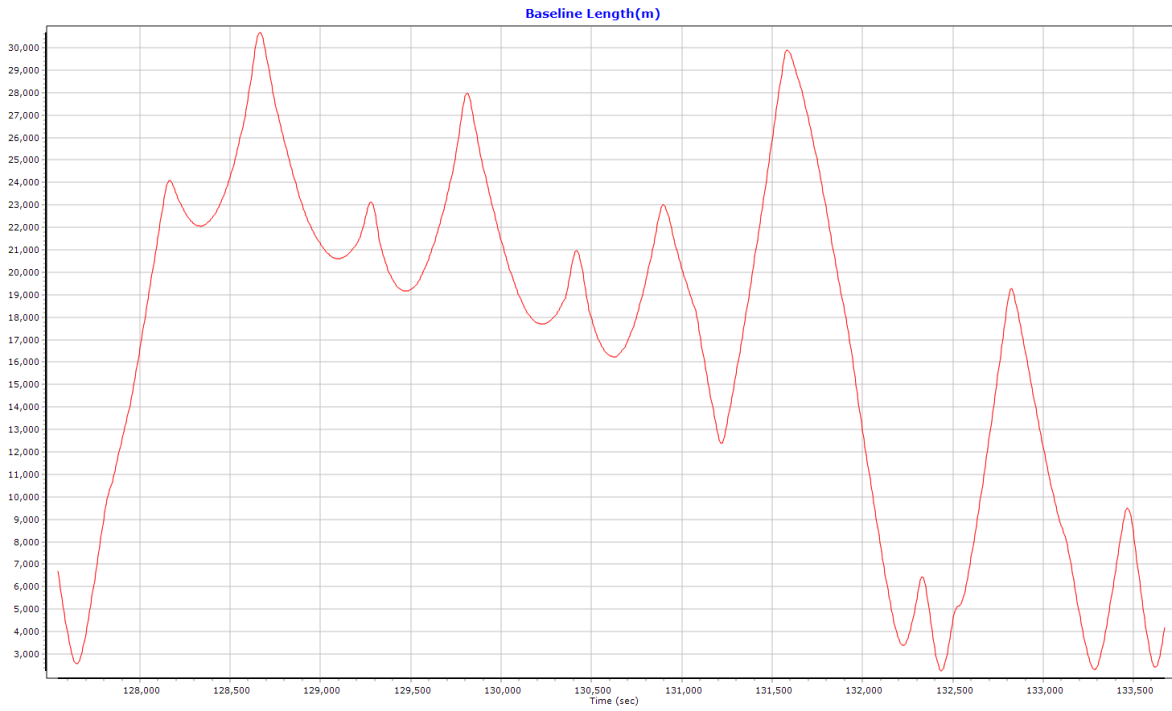
Standard Deviation: <3cm 10cm 50cm 1m 10m

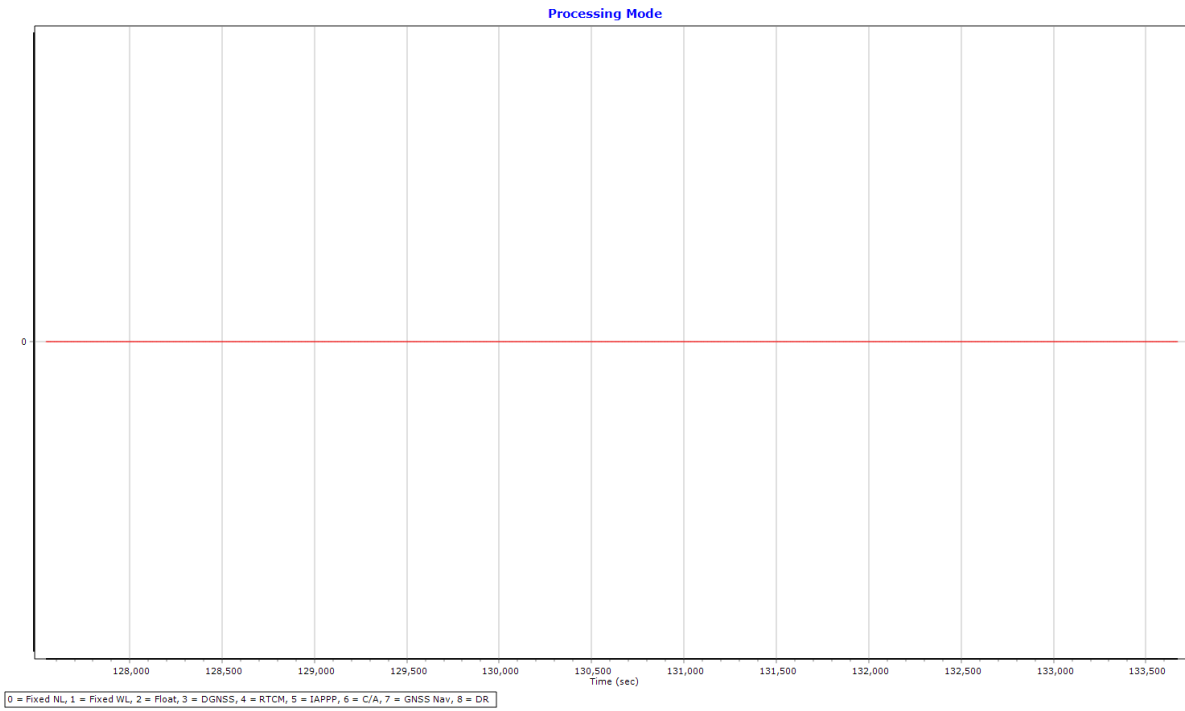
OK Cancel



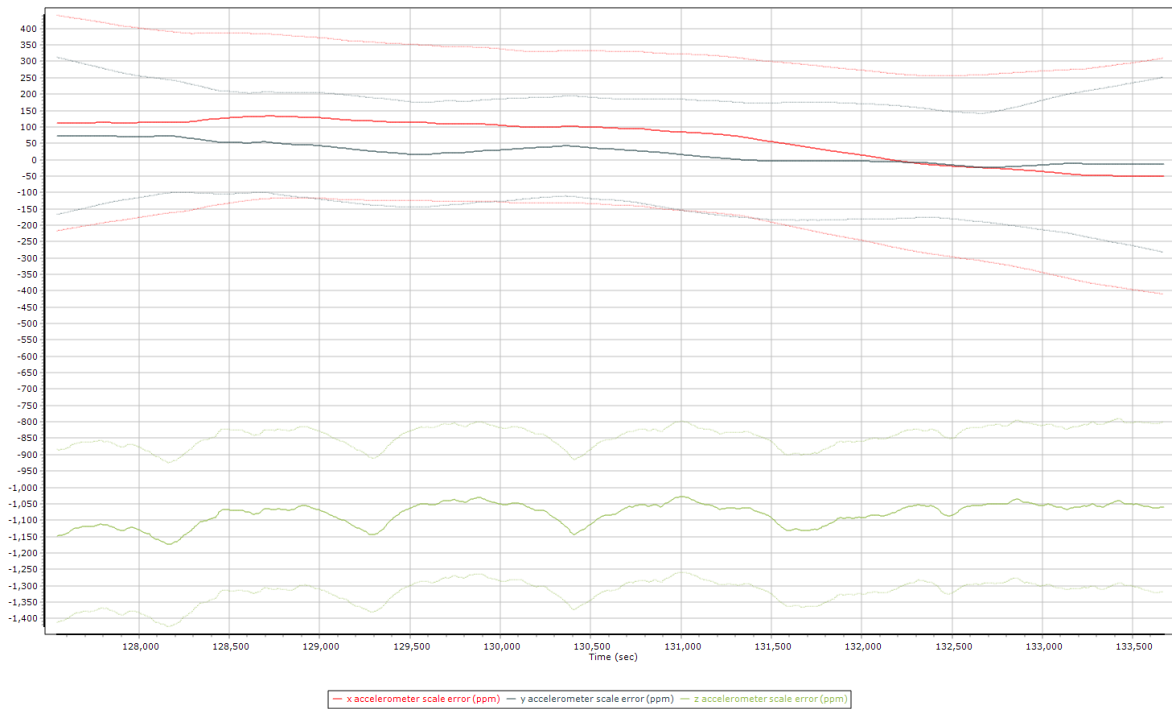
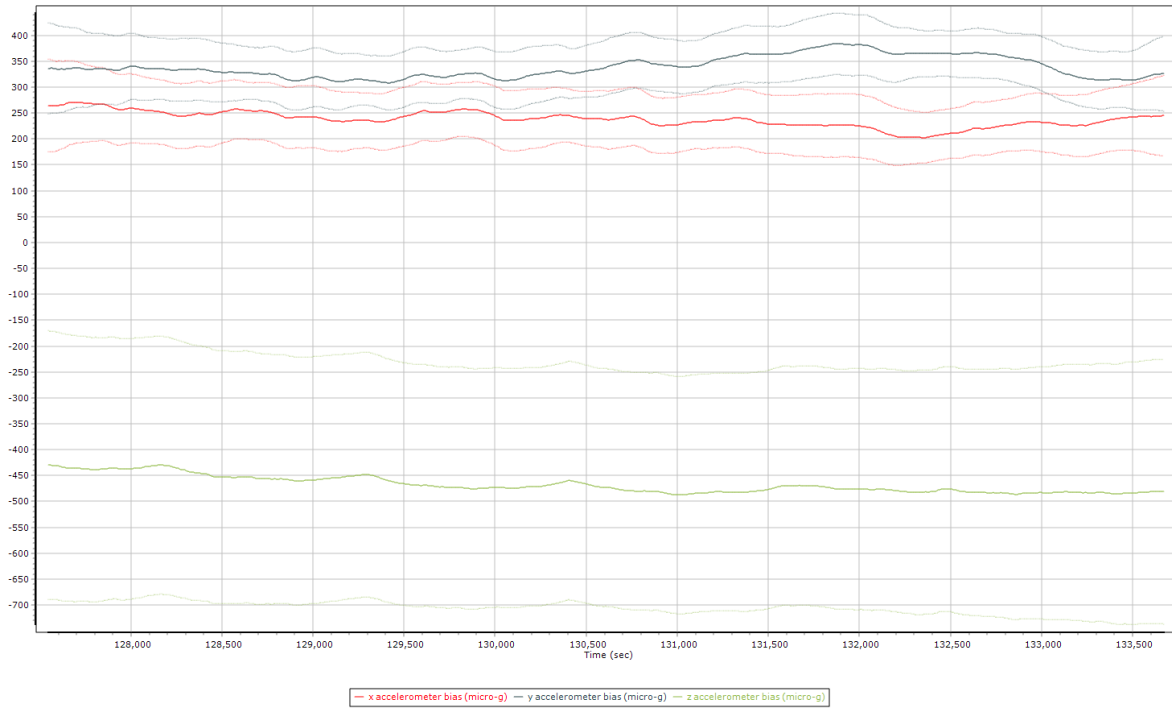


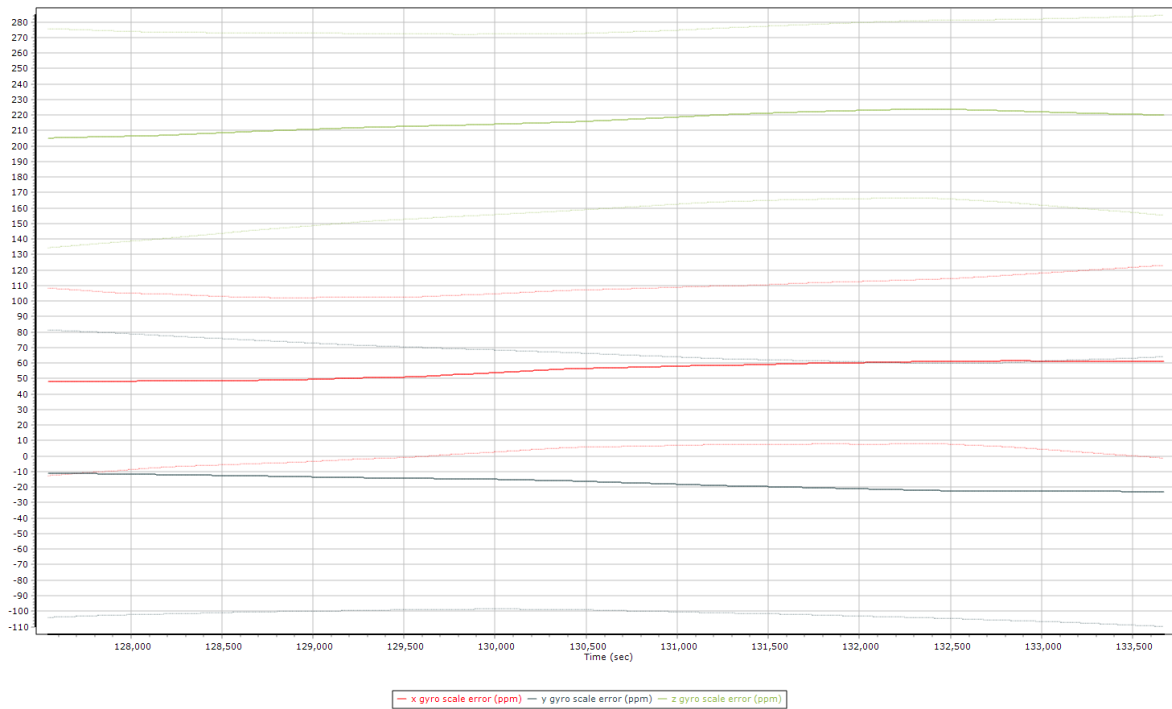
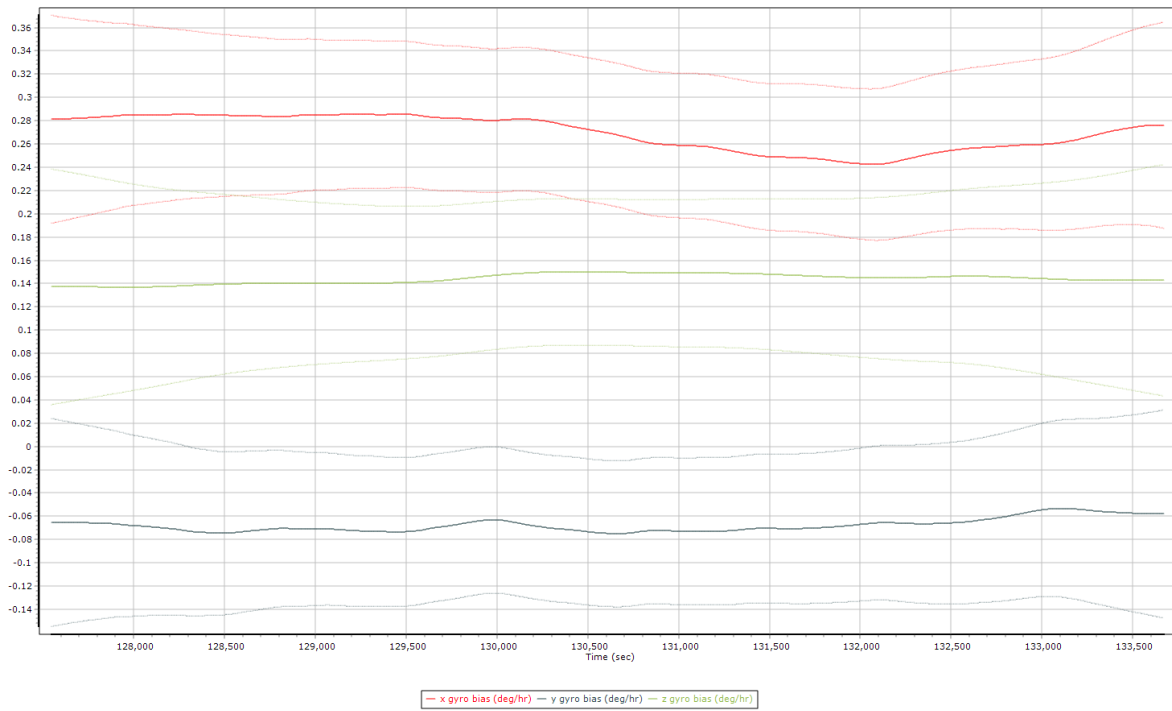




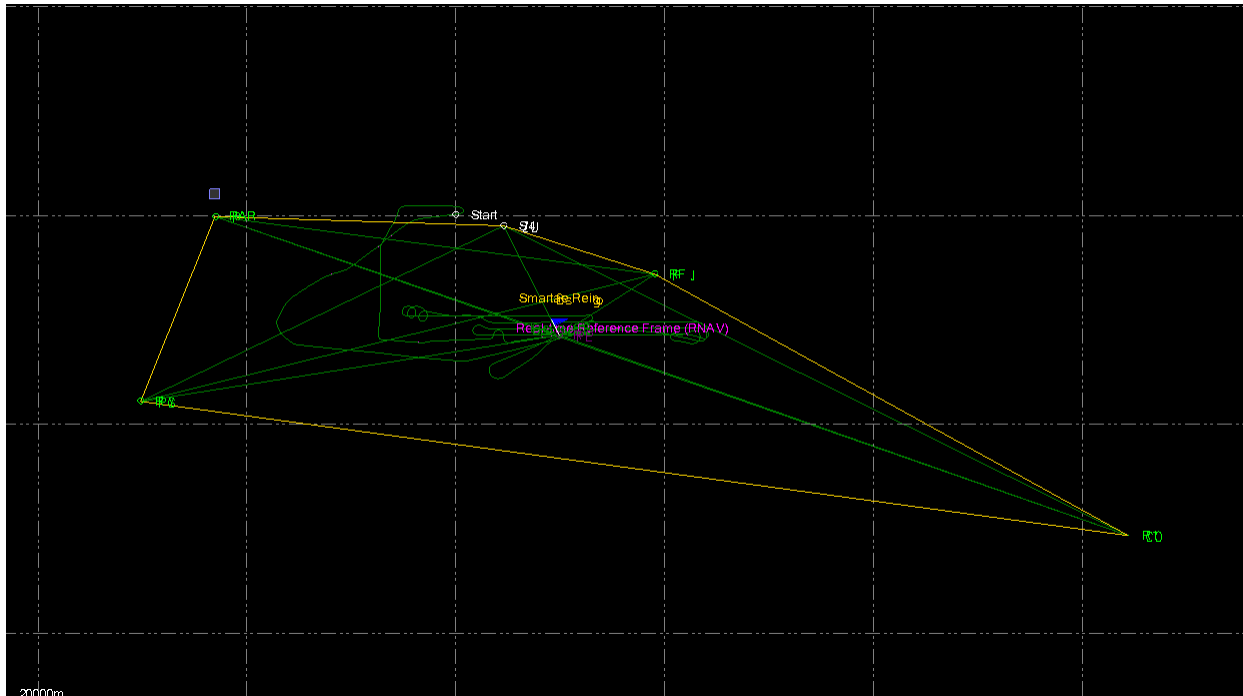


Sensor Errors





RBV19093A



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: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 m	Z: 0.000 deg

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

OK Cancel

Project Settings

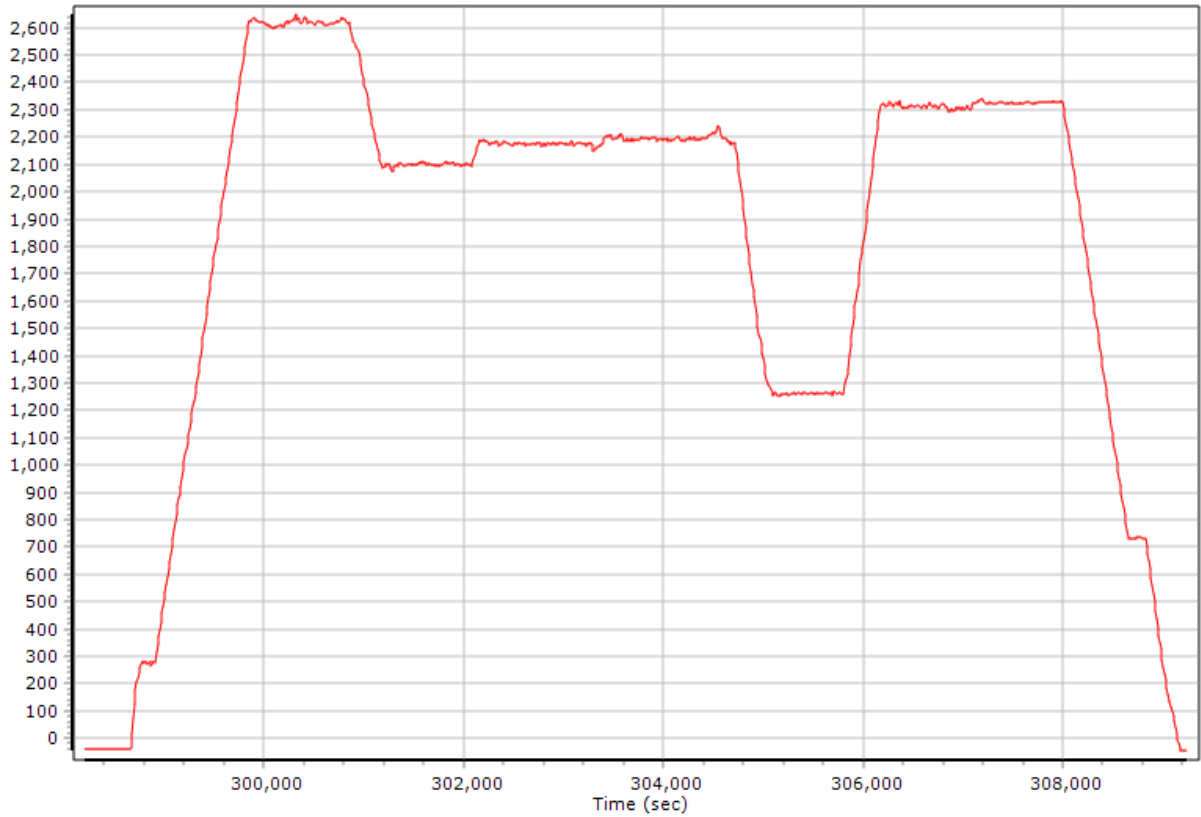
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
- Timing**

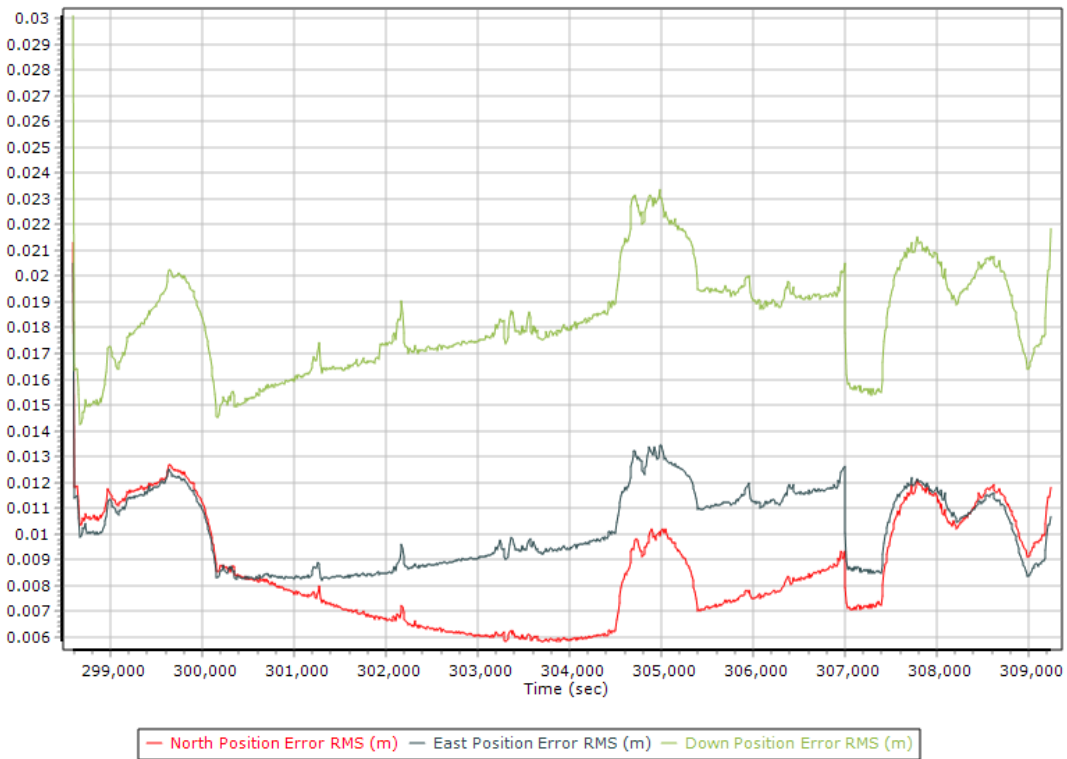
Timing

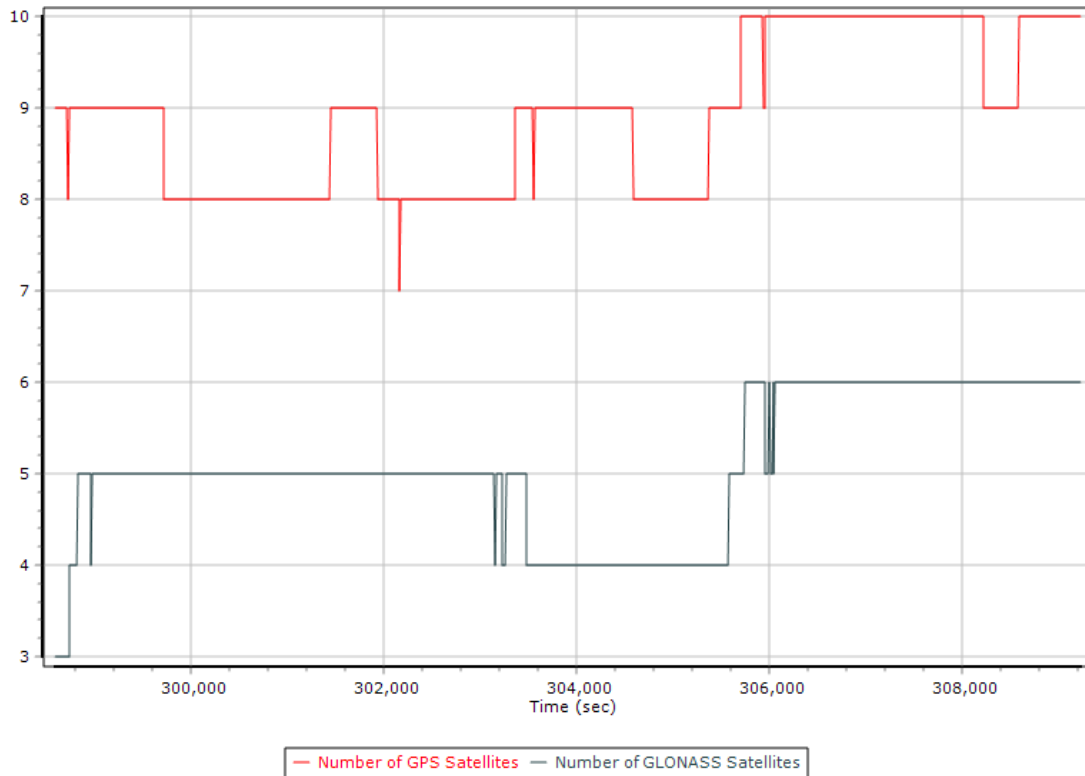
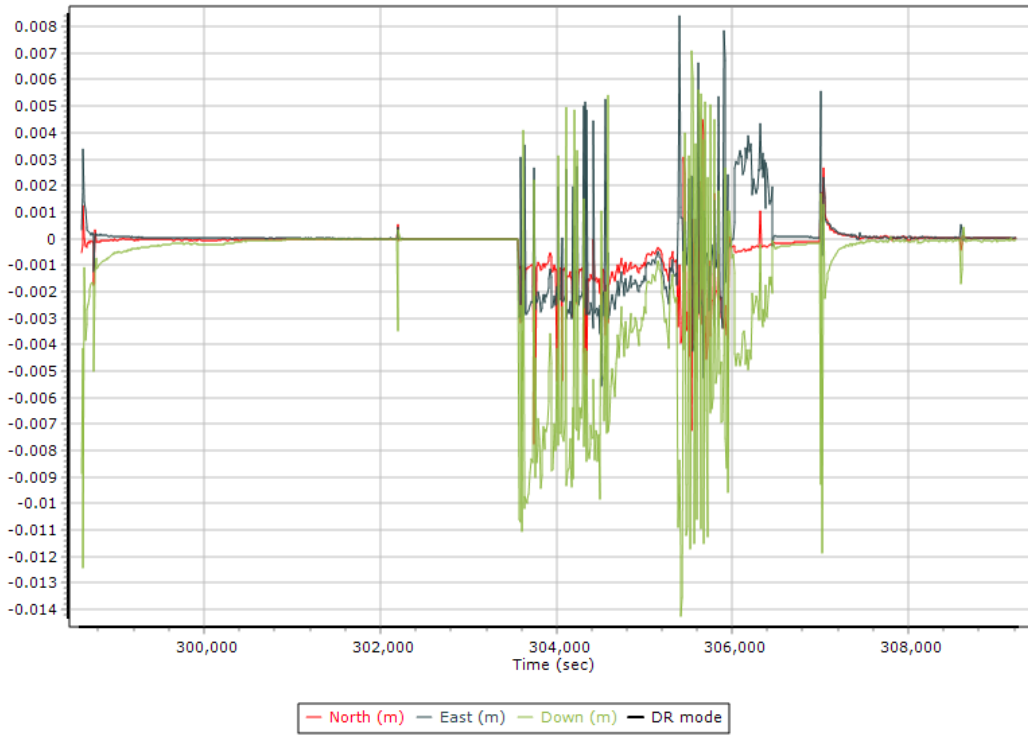
Start 298209.000
End 309239.000
 Entire time interval
 Seconds of start week
UTC Offset 18.000

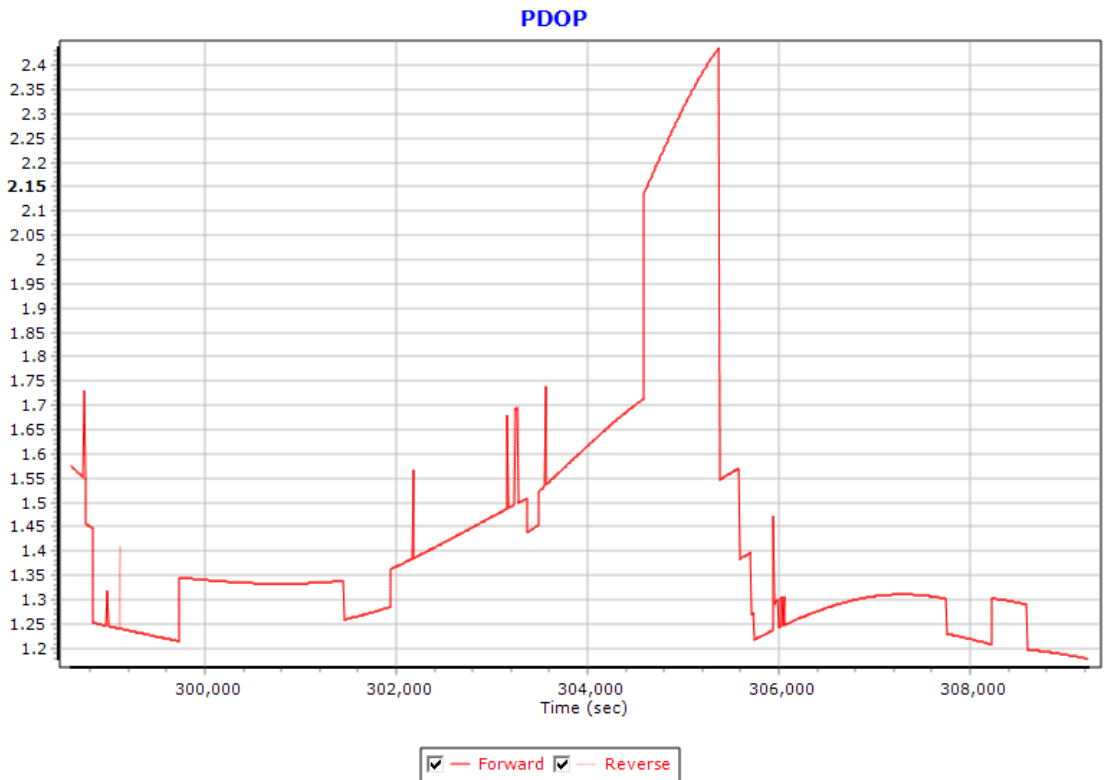
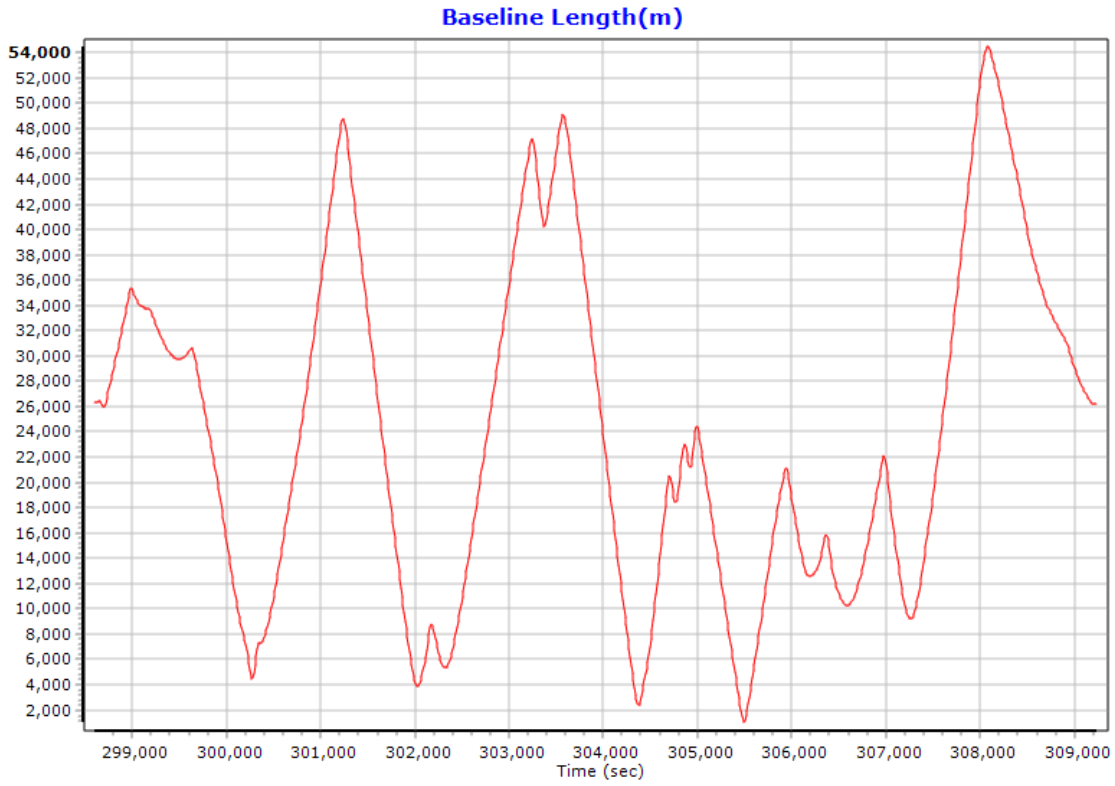
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

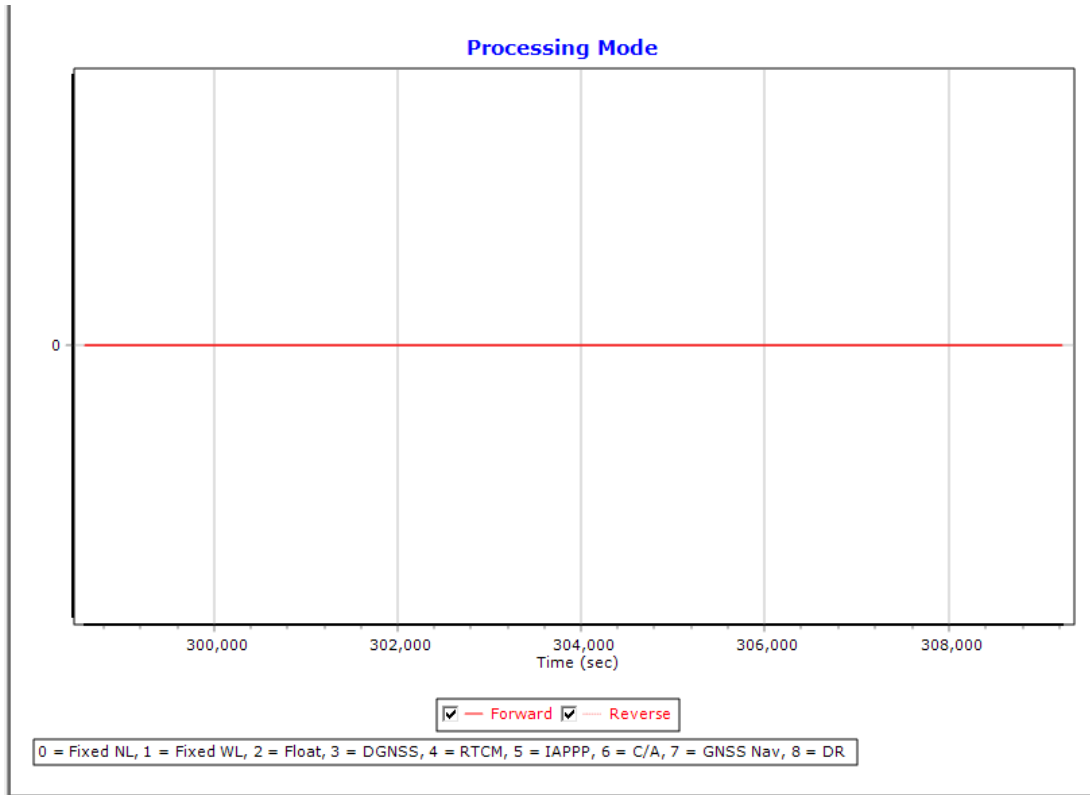
Altitude (m)



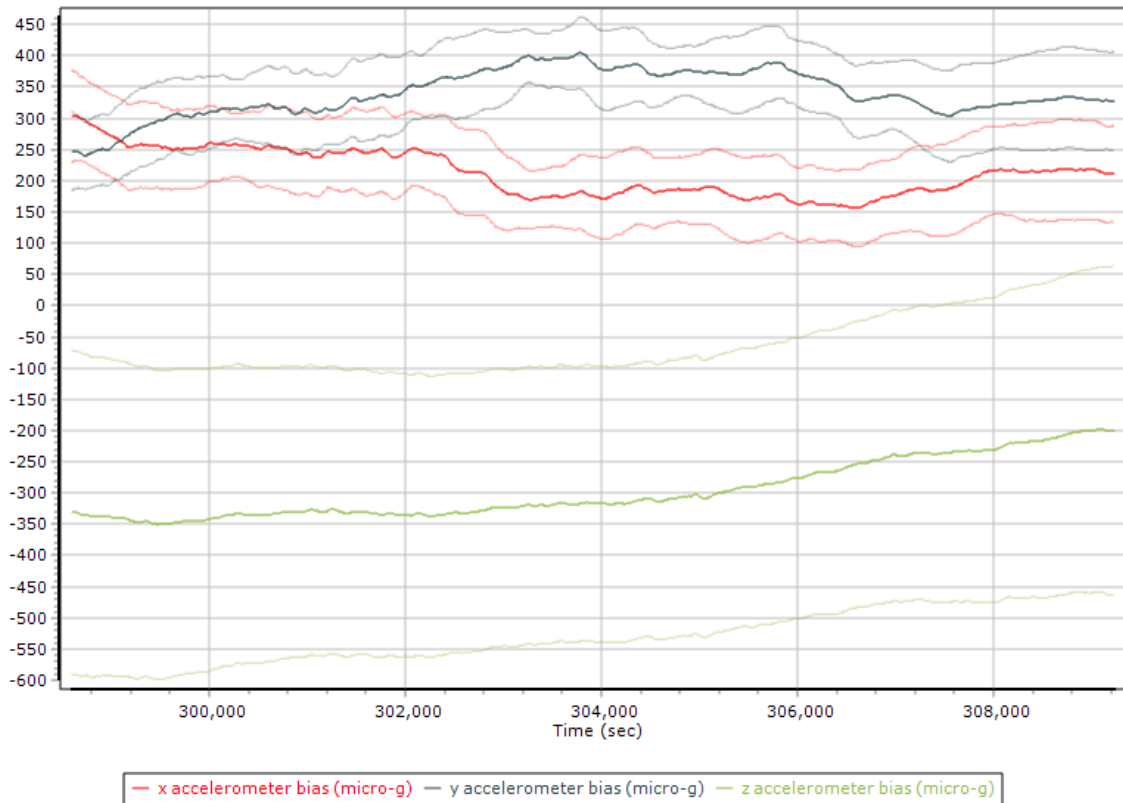


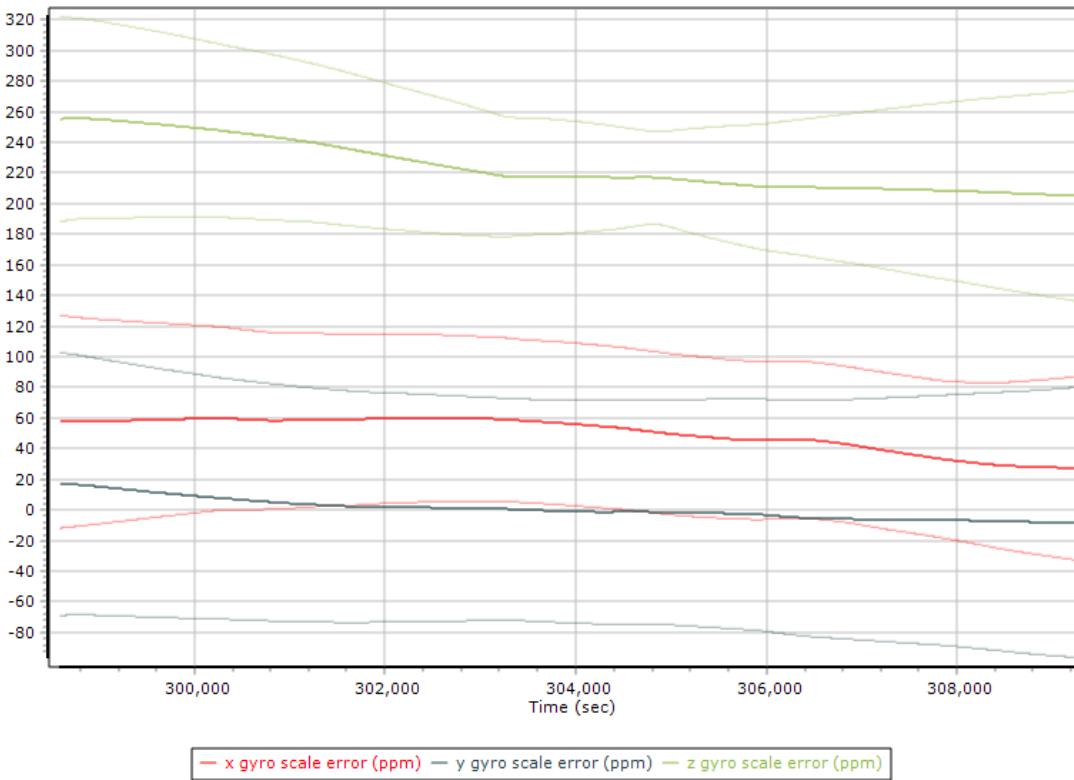
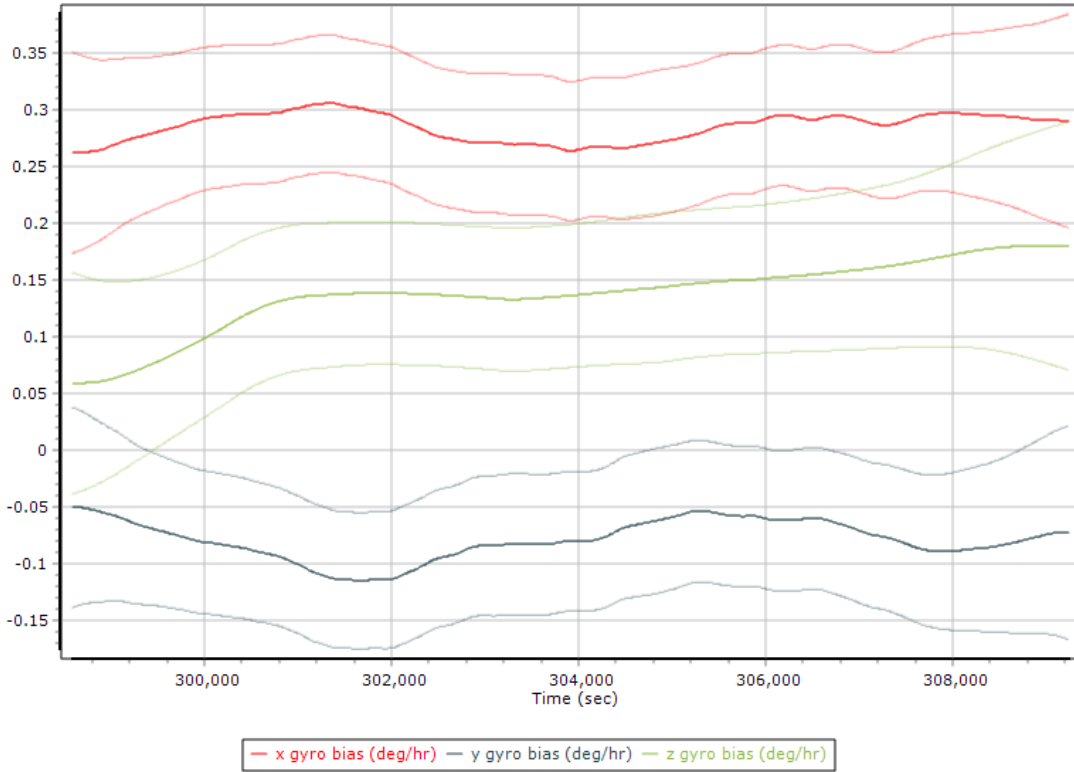




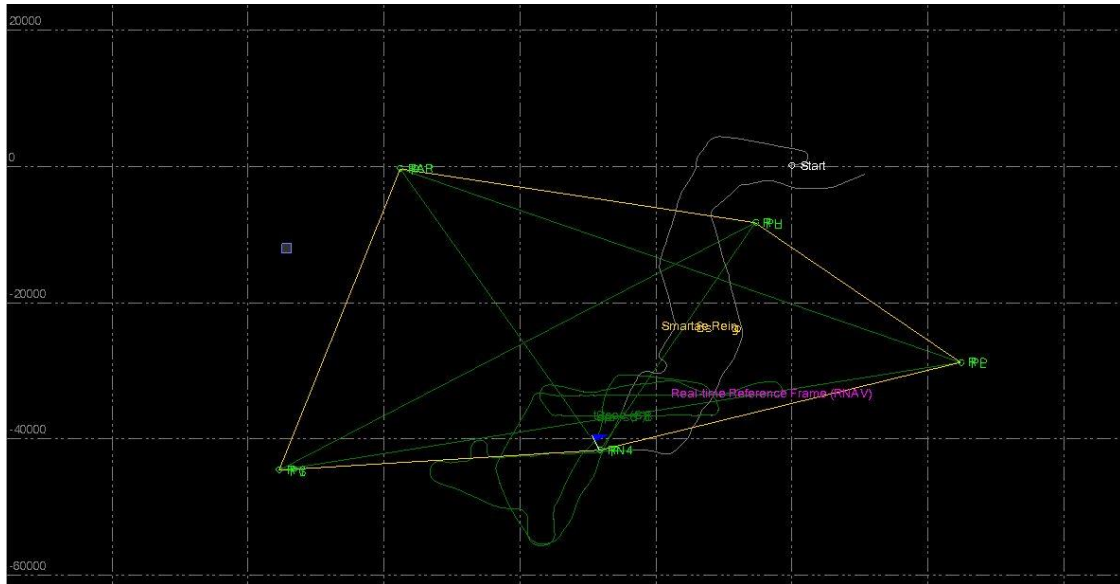


Sensor Errors





RBV19099B



Project Settings

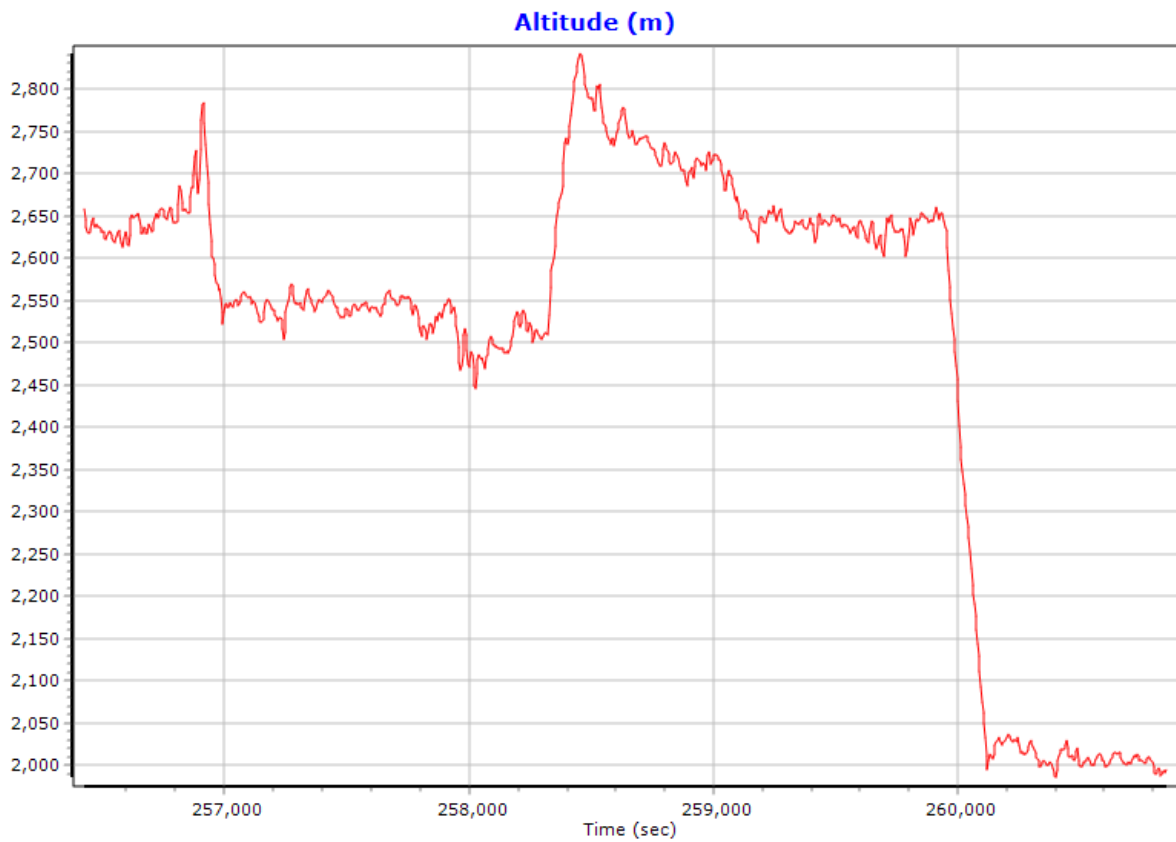
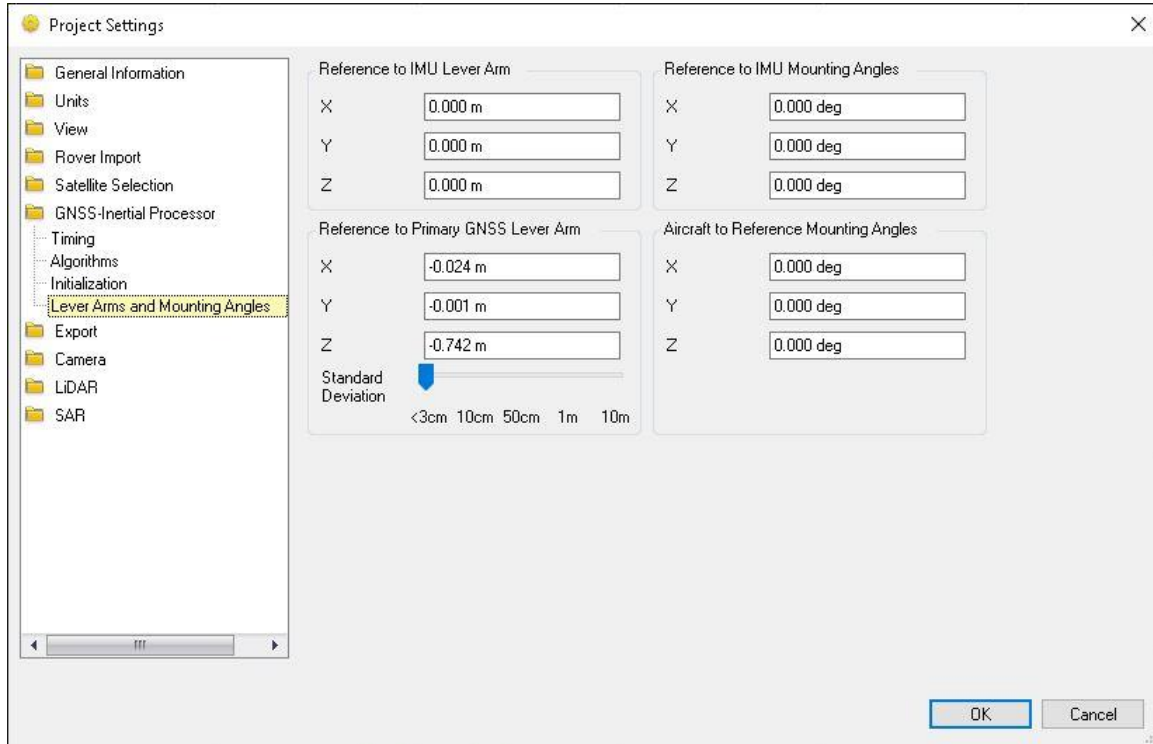
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
 - Export
 - Camera
 - LIDAR
 - SAR

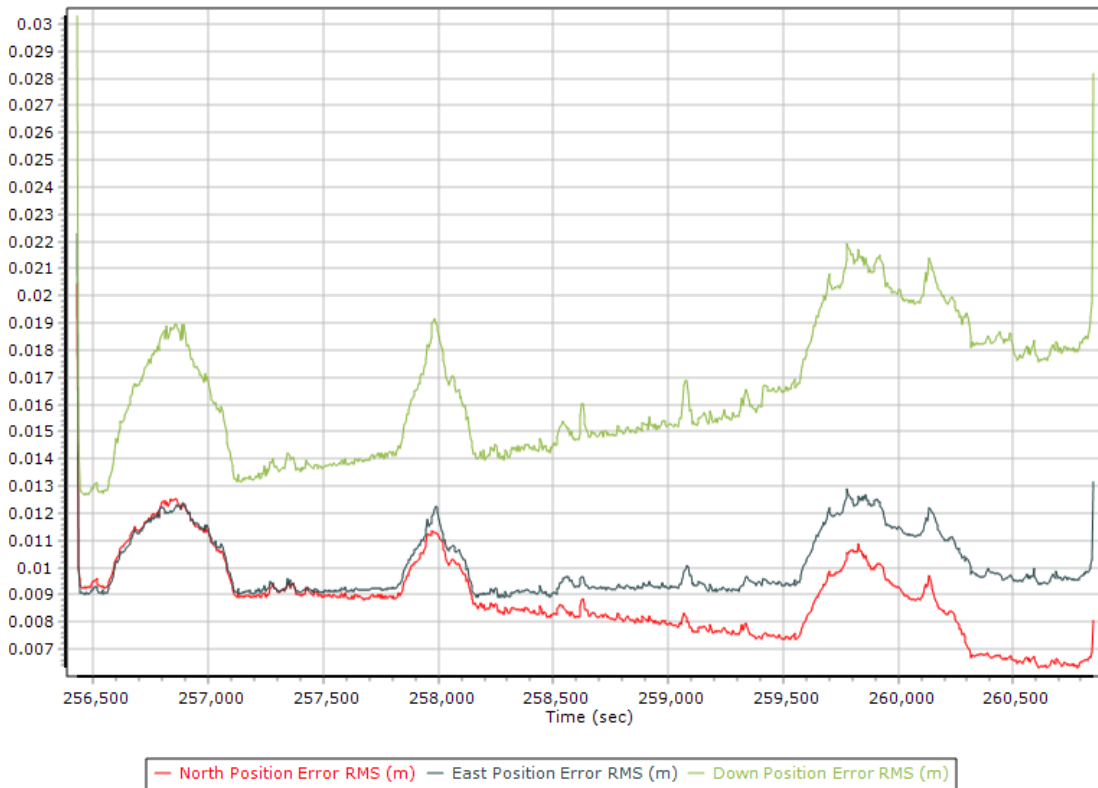
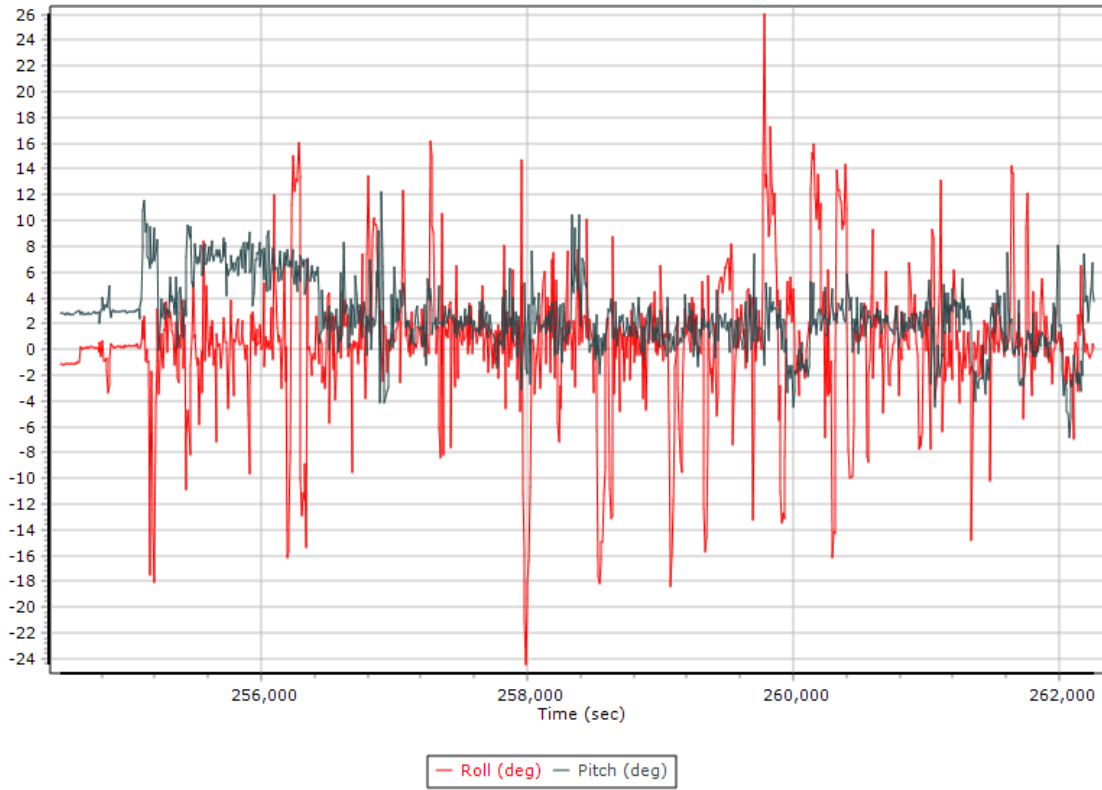
Reference to IMU Lever Arm	Reference to IMU Mounting Angles
X: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

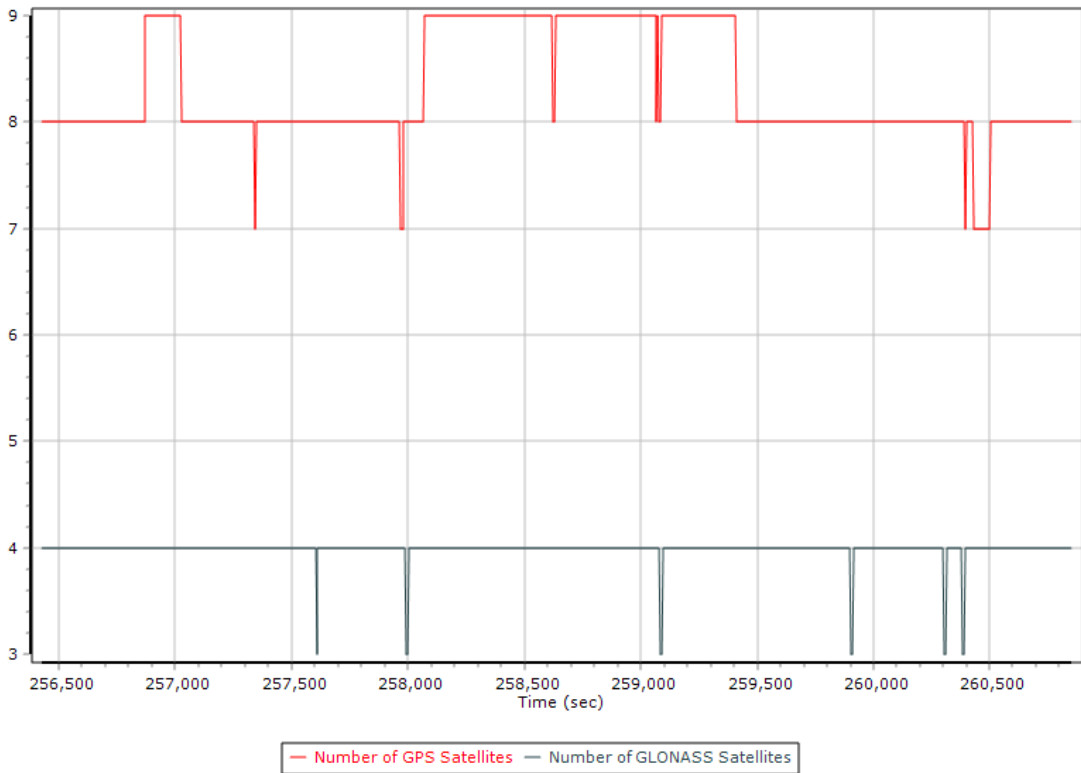
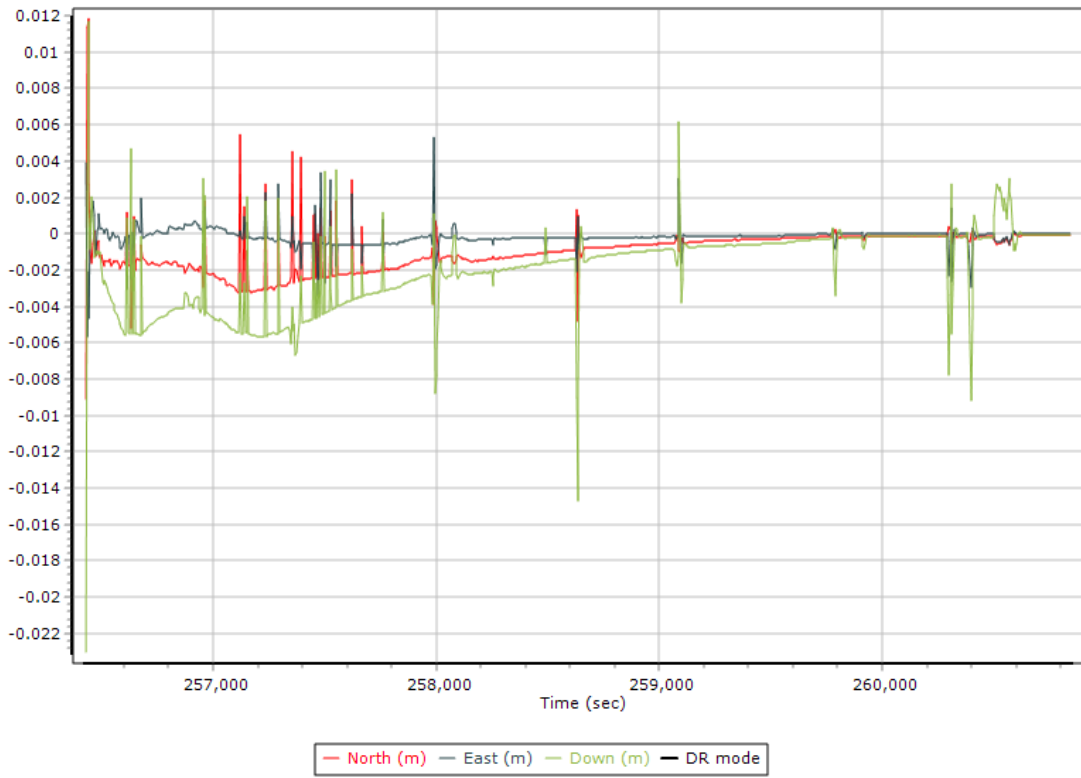
Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.024 m	X: 0.000 deg
Y: -0.001 m	Y: 0.000 deg
Z: -0.742 m	Z: 0.000 deg

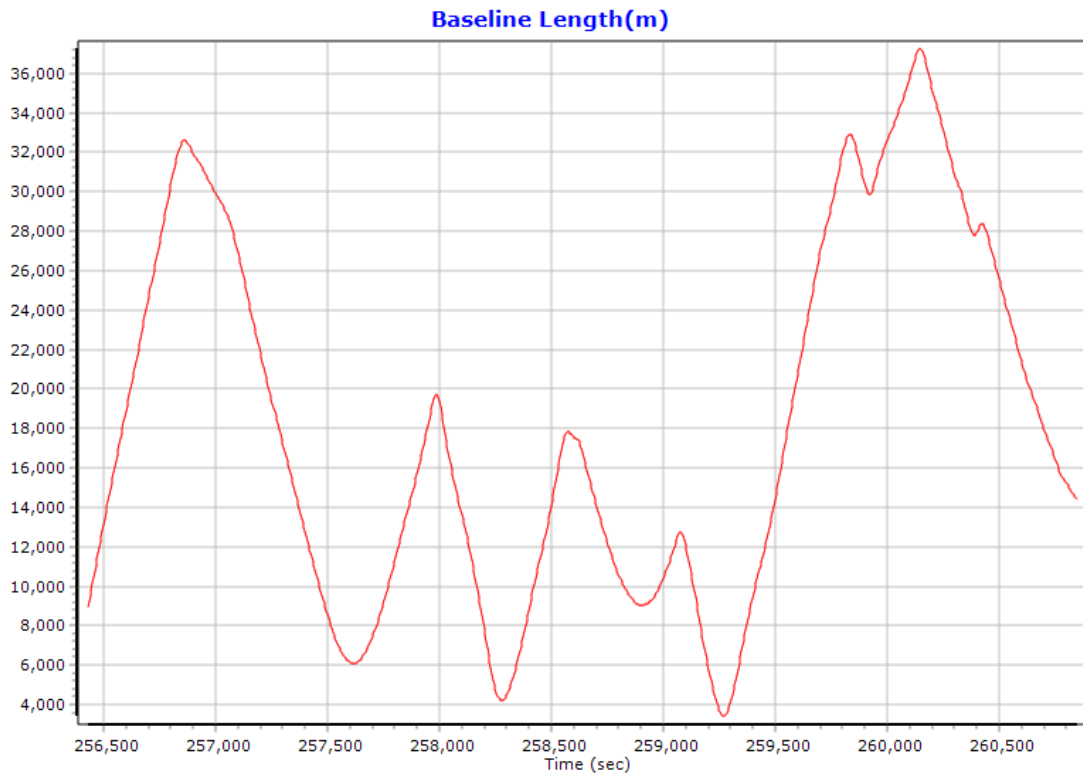
Standard Deviation: <3cm 10cm 50cm 1m 10m

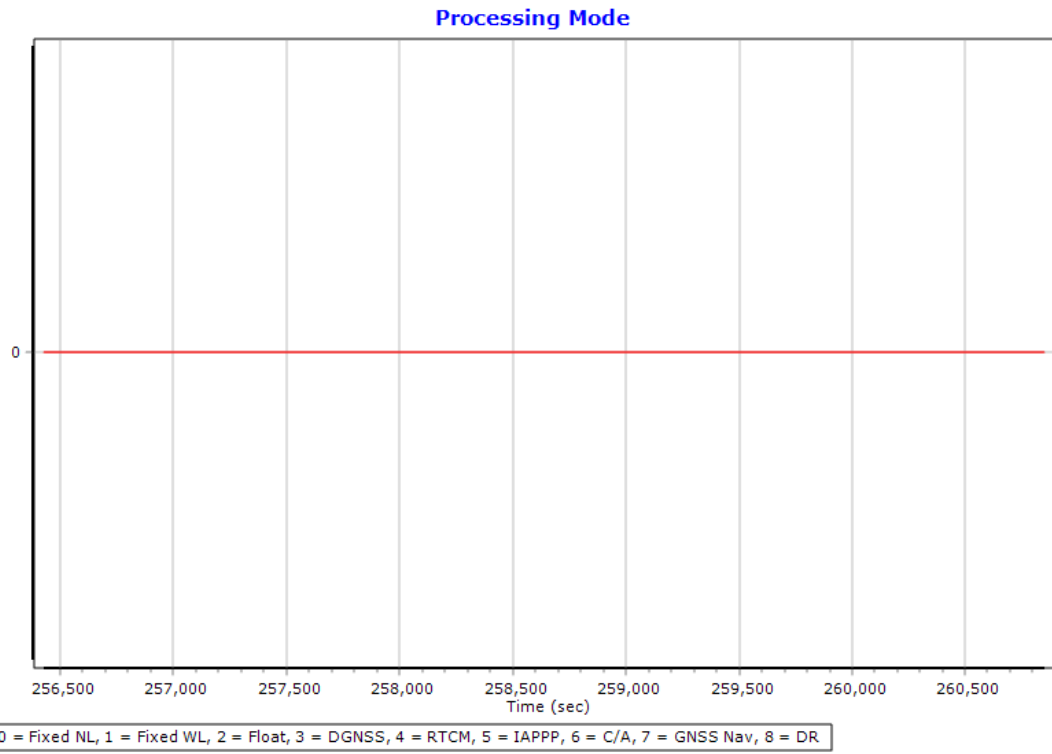
OK



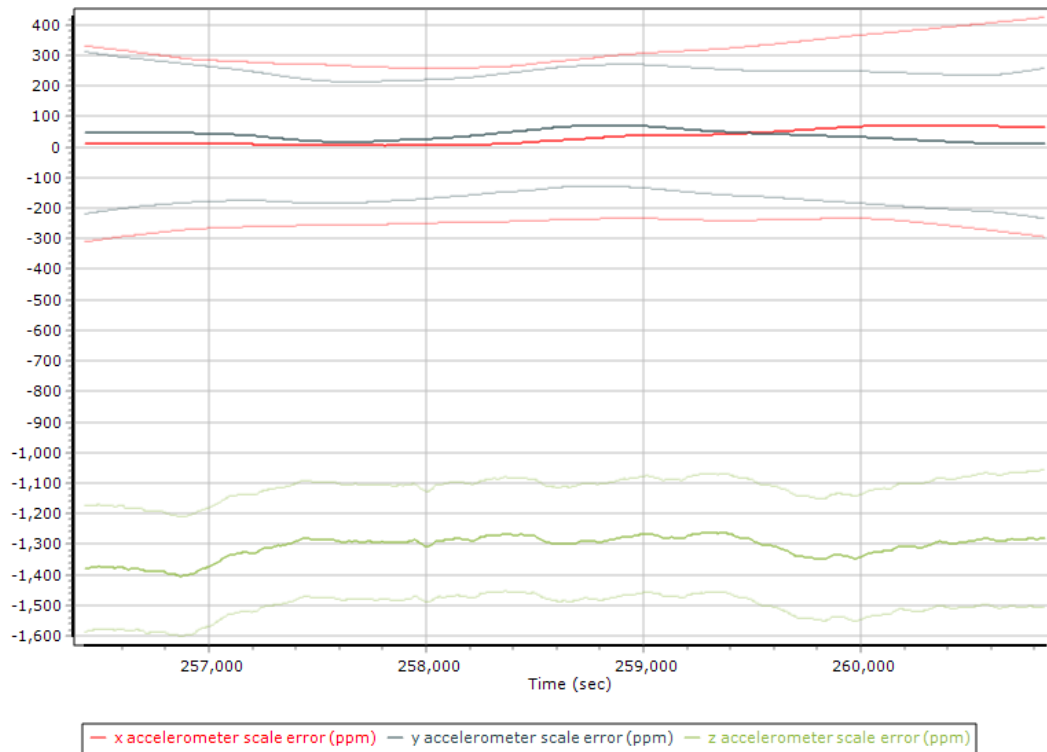
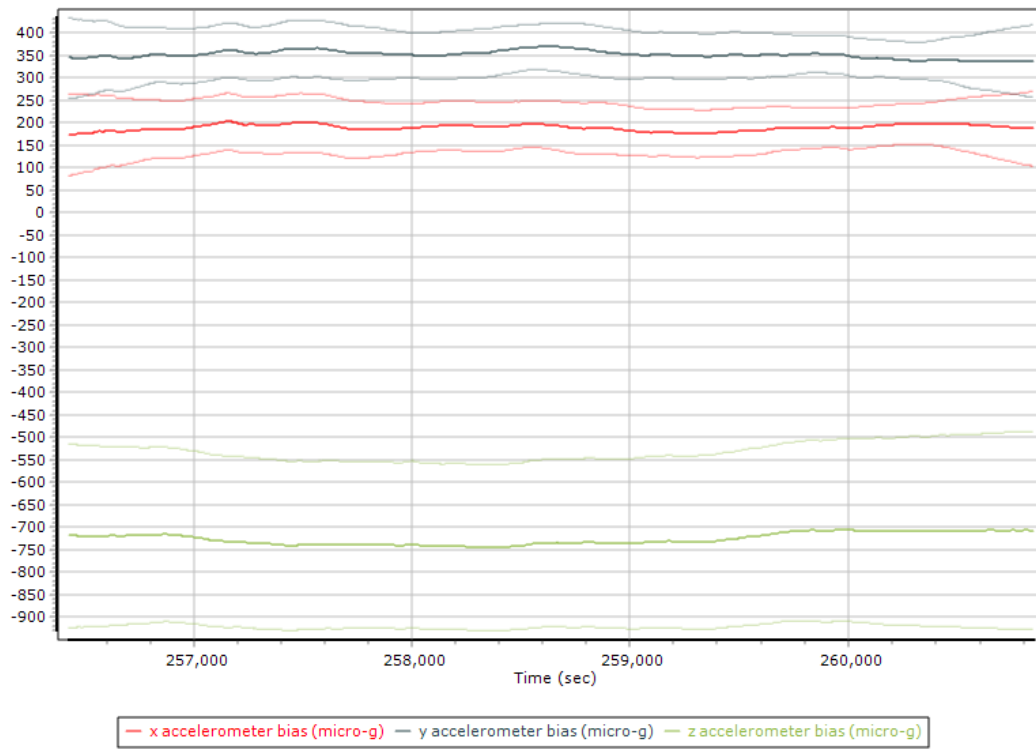


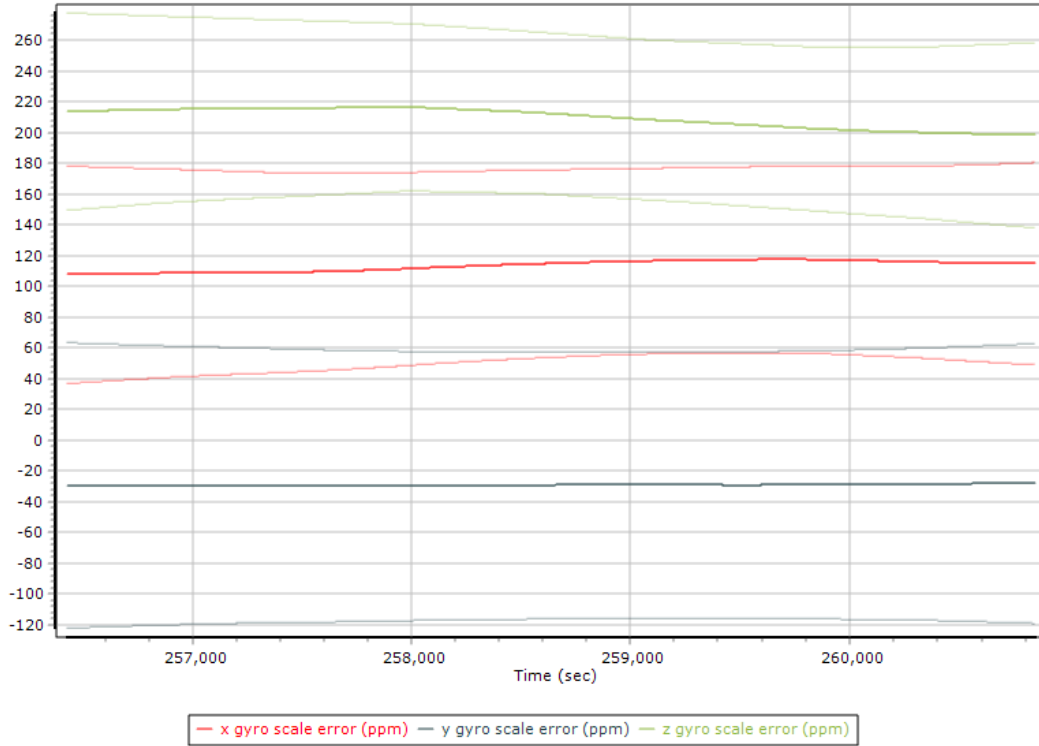
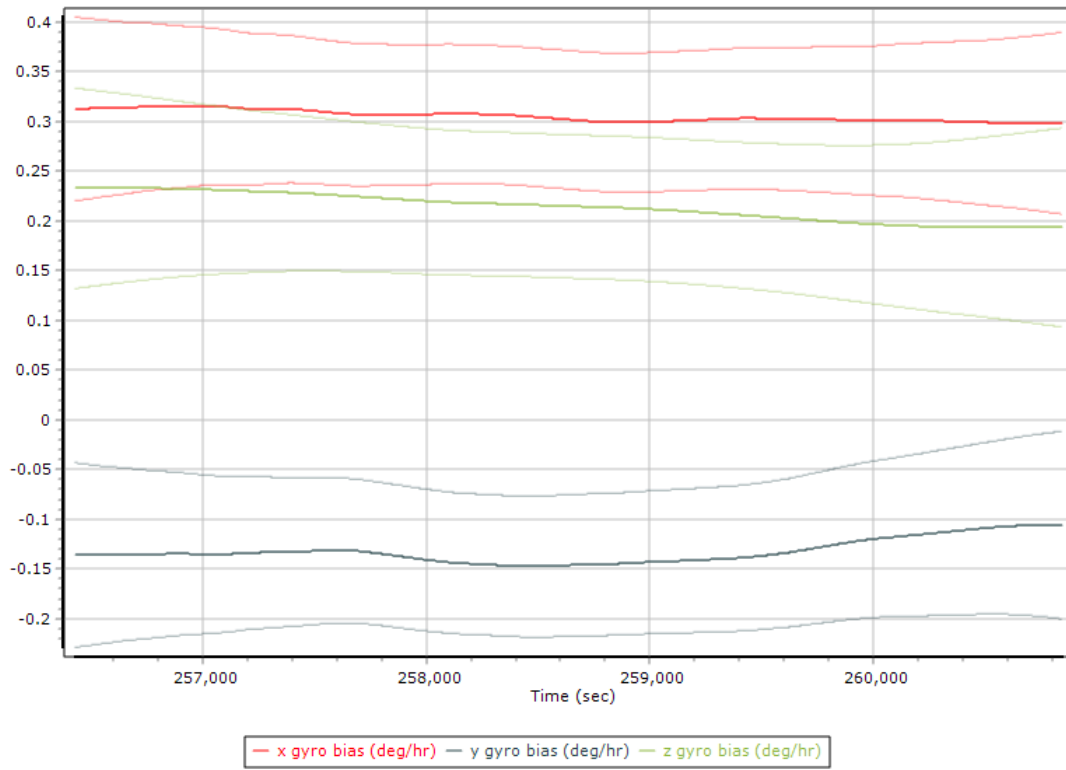




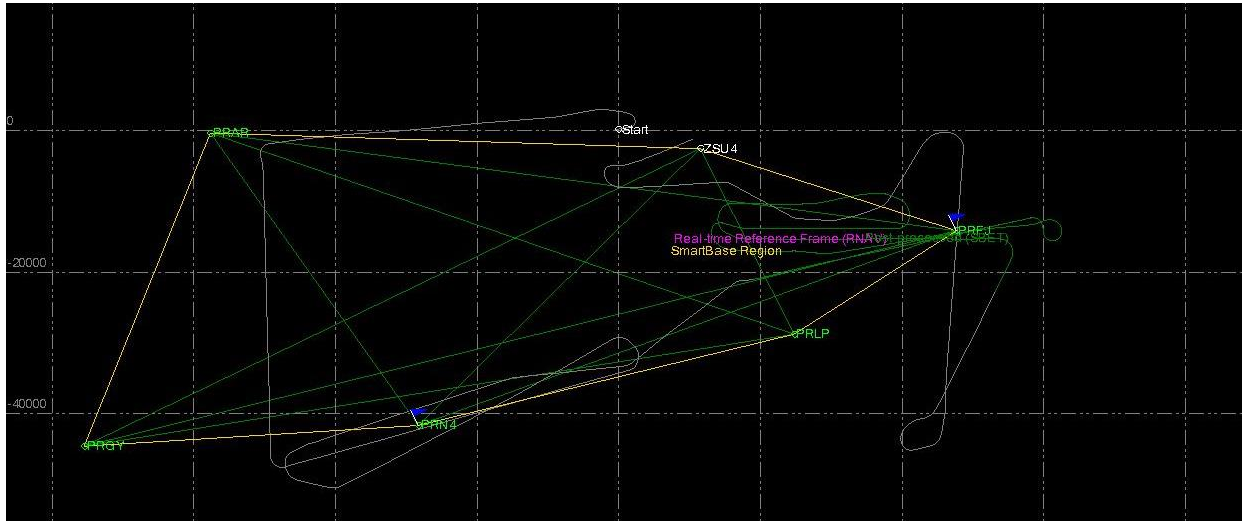


Sensor Errors





XXS19102A



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: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: 0.039 m	X: 0.000 deg
Y: 0.120 m	Y: 0.000 deg
Z: -0.777 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

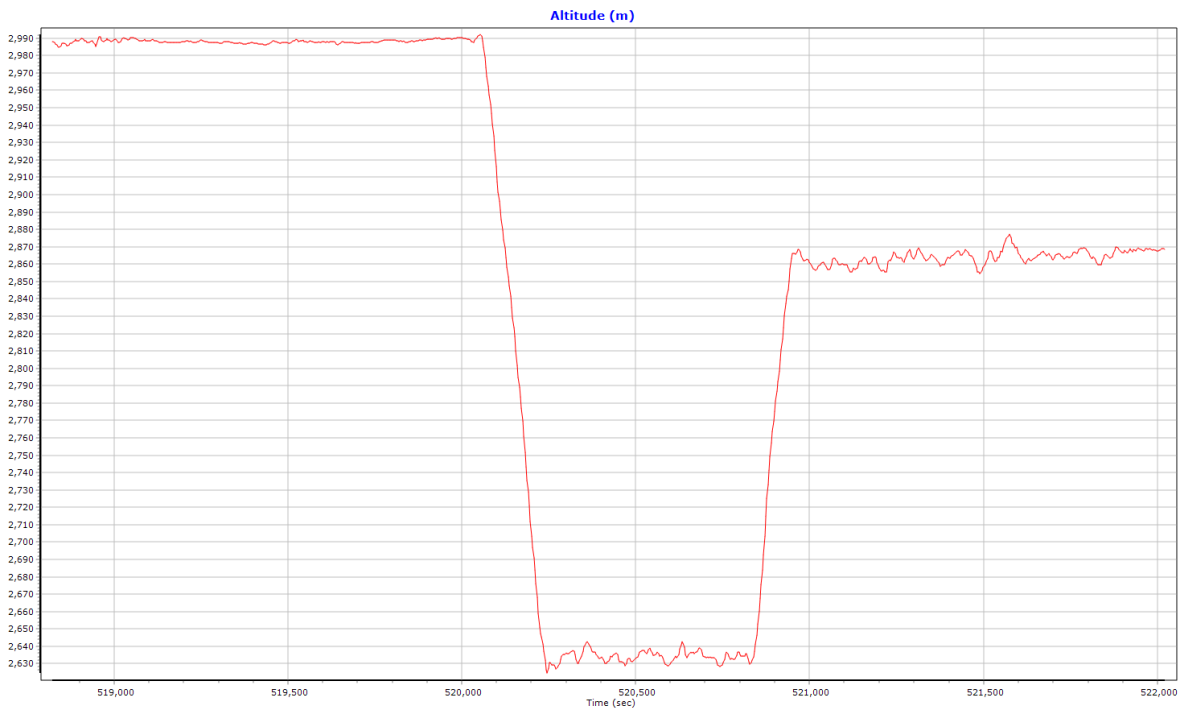
Start: 518820.984
End: 522022.643

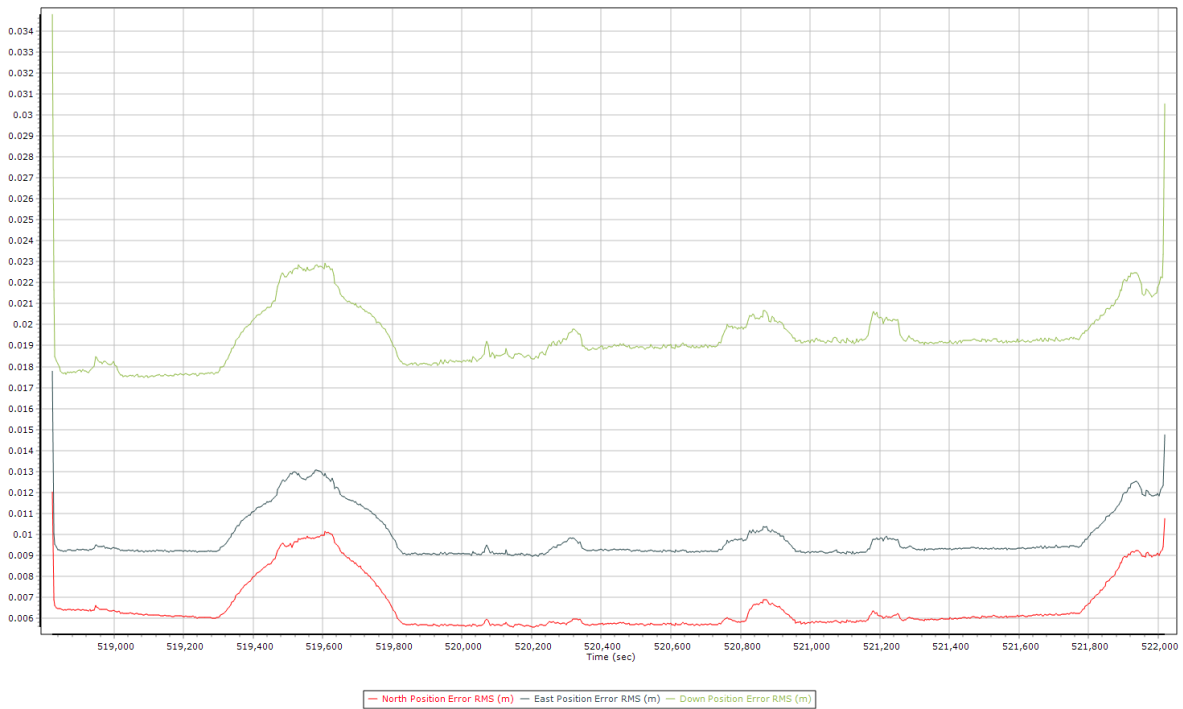
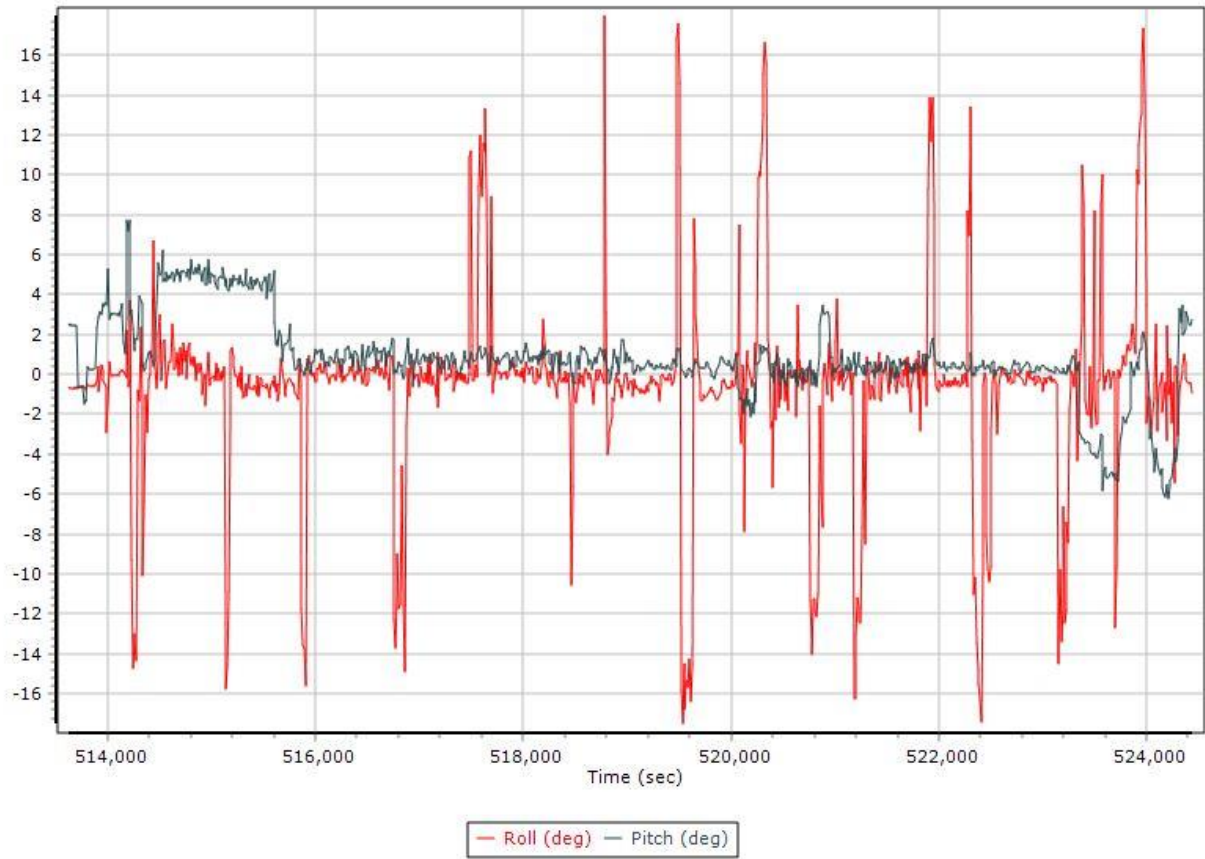
Entire time interval
 Seconds of start week

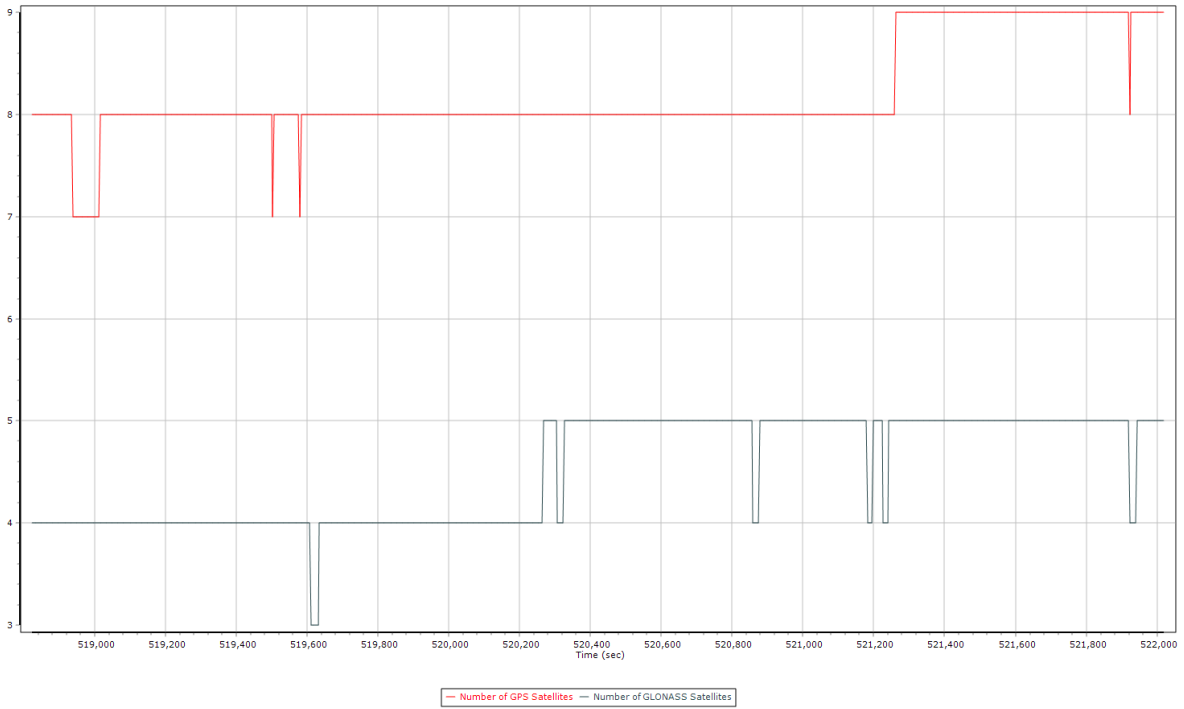
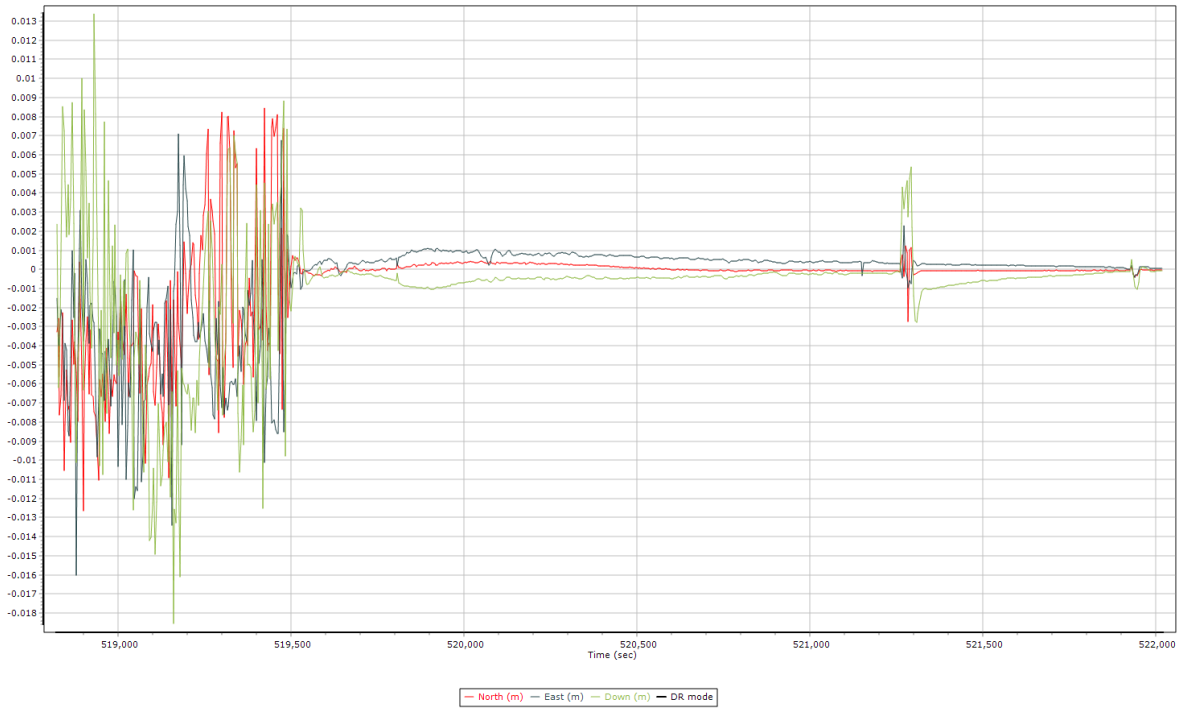
UTC Offset: 18.000

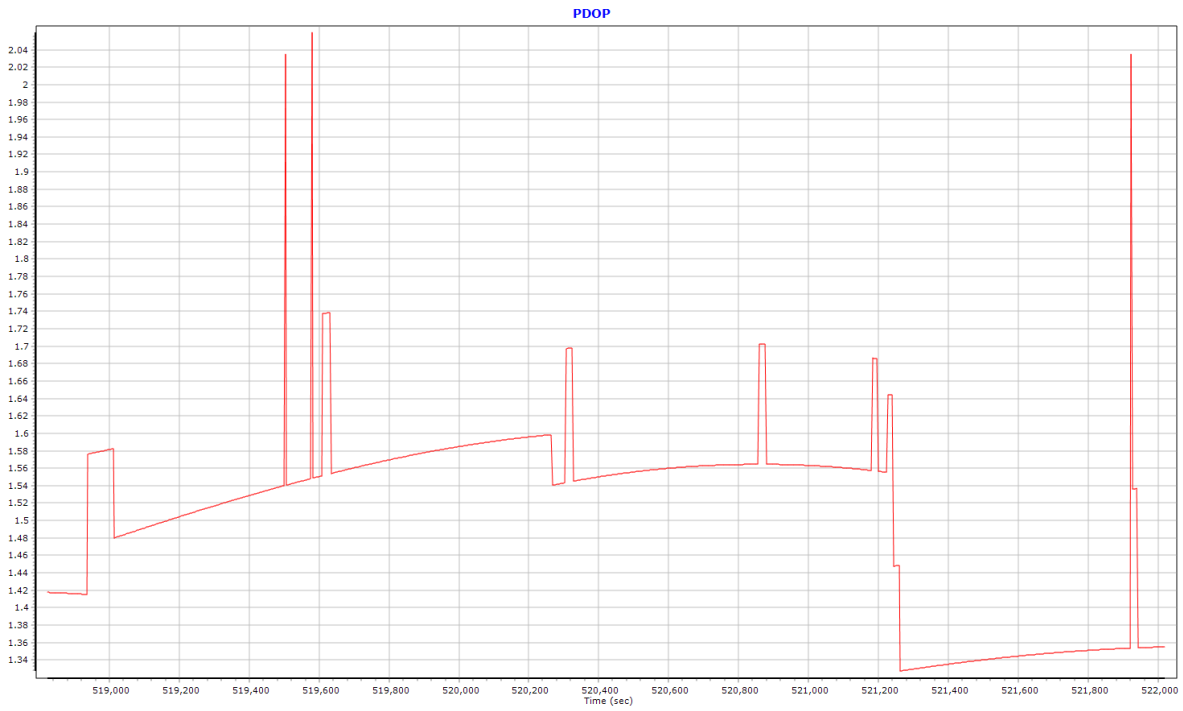
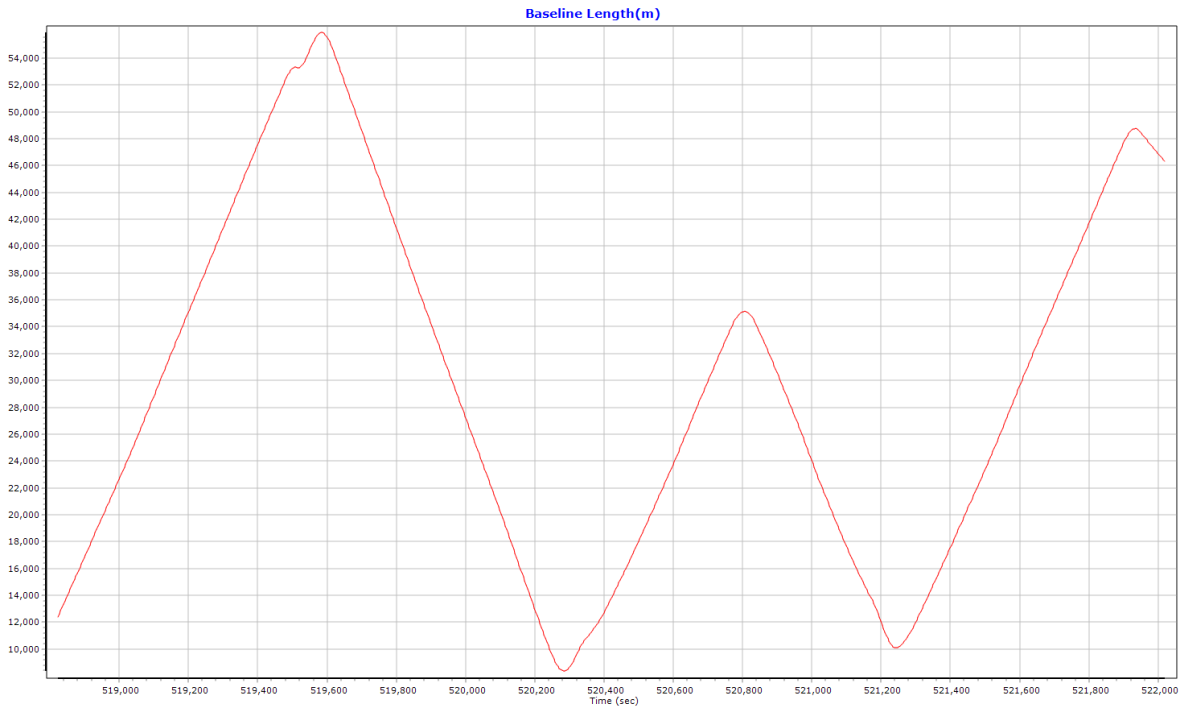
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel



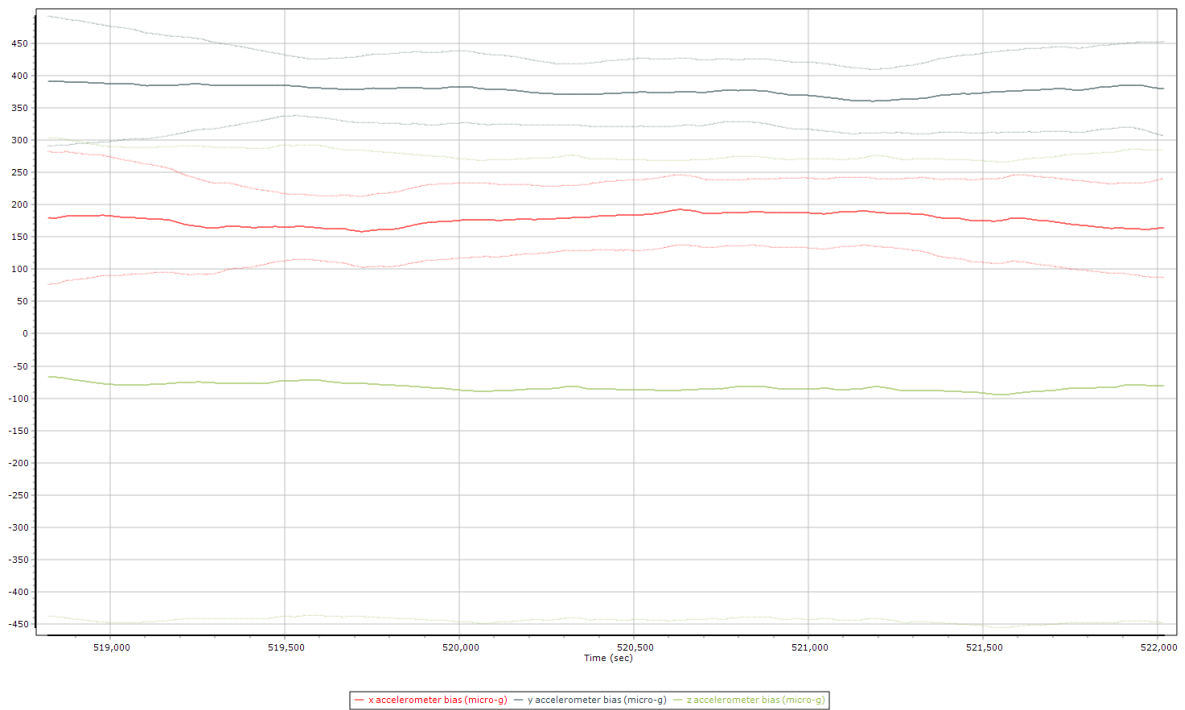


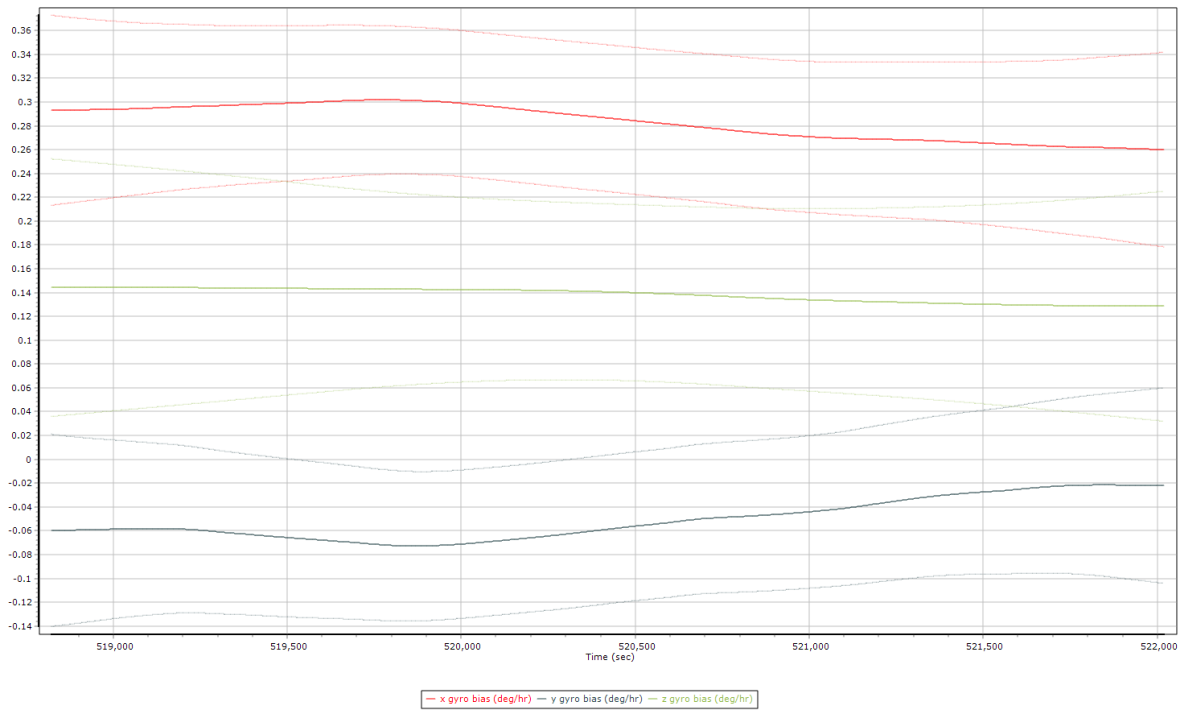


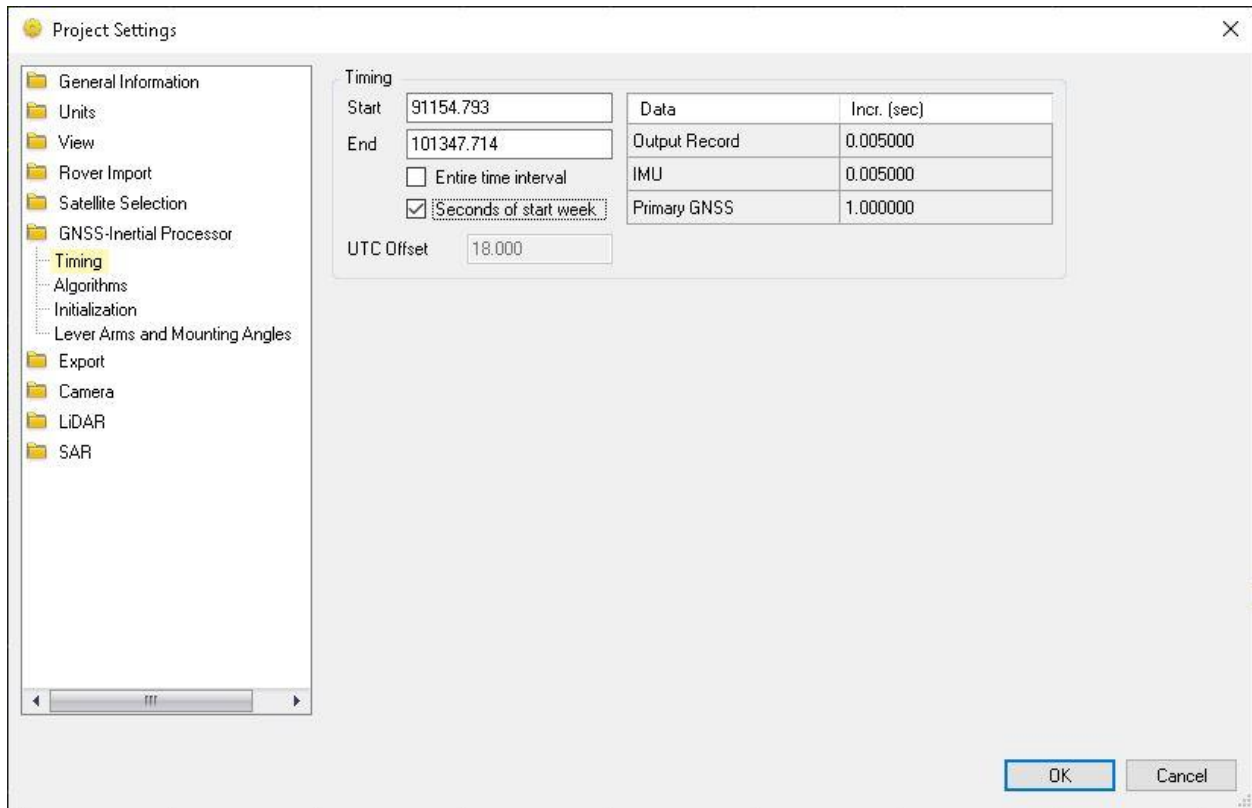
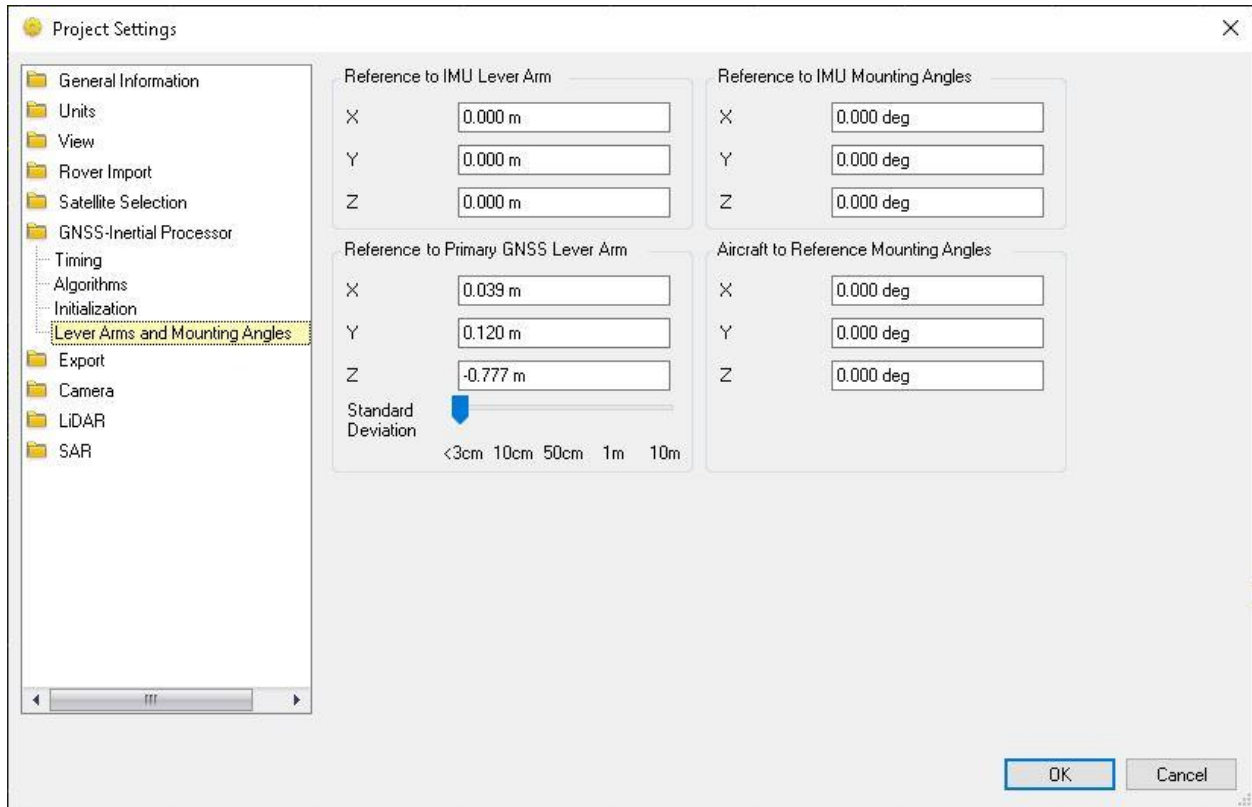


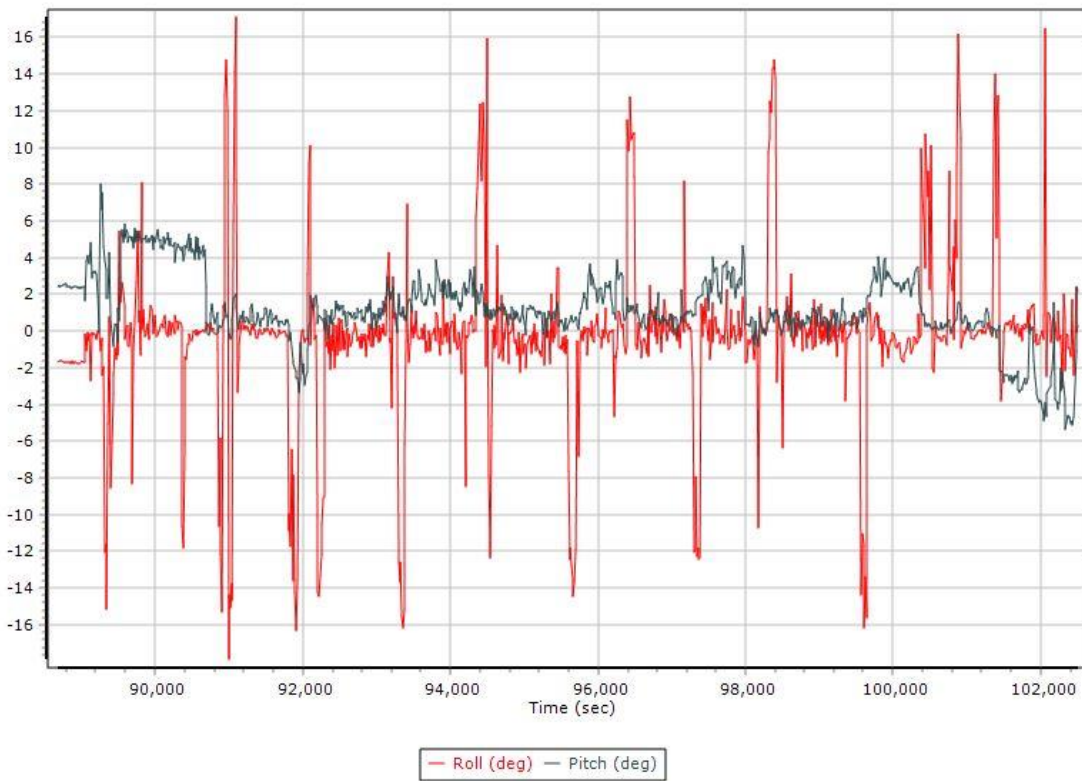
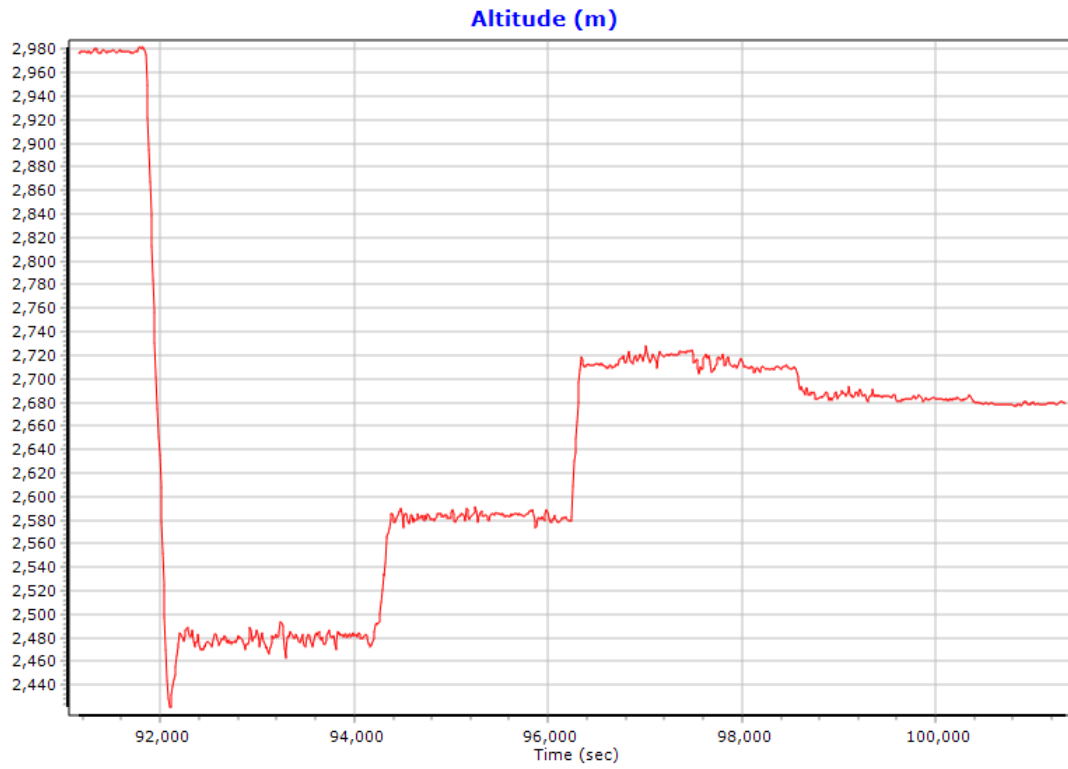


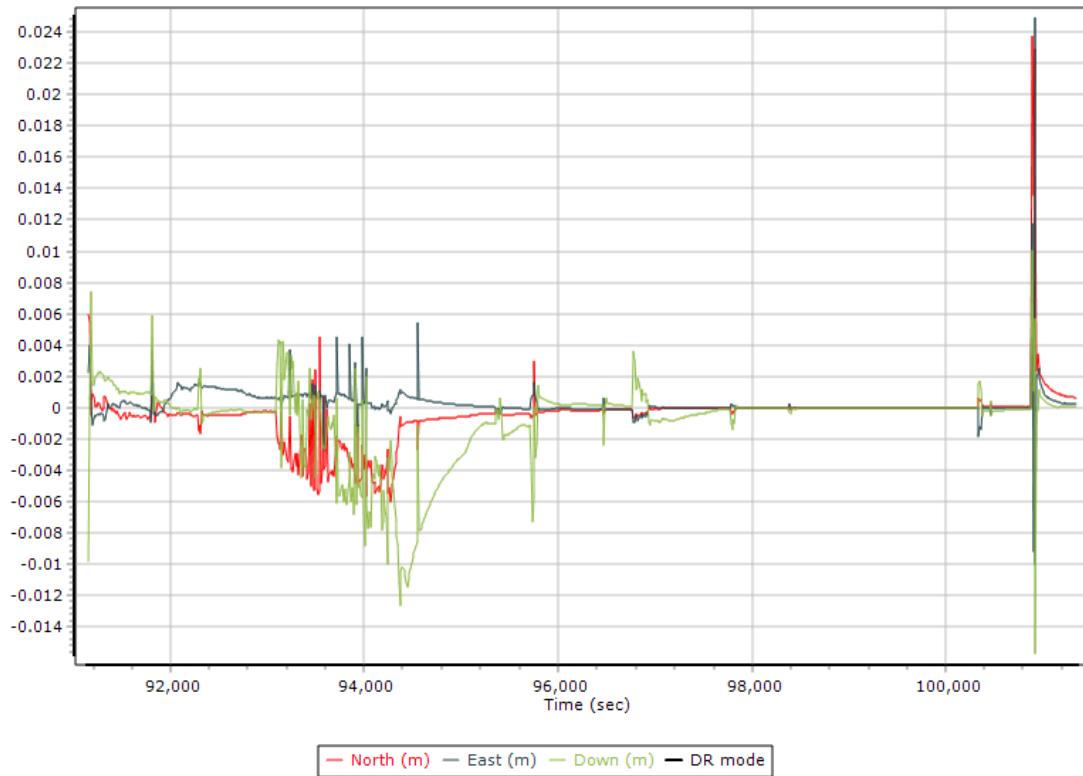
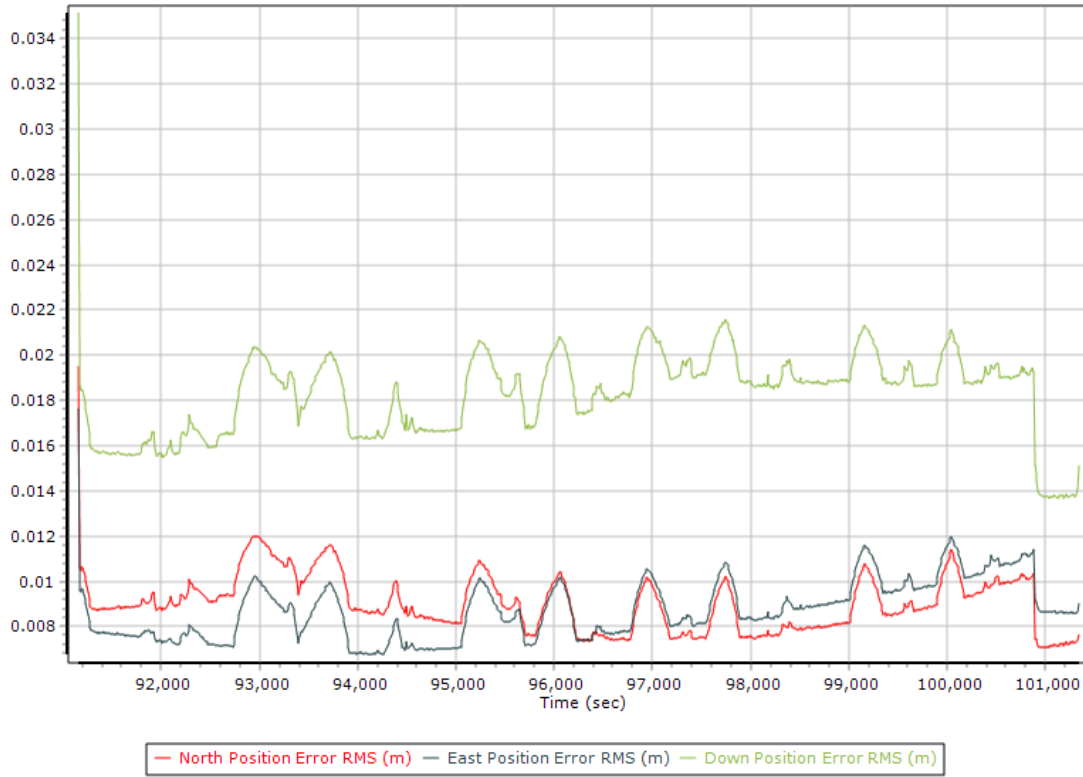
Sensor Errors

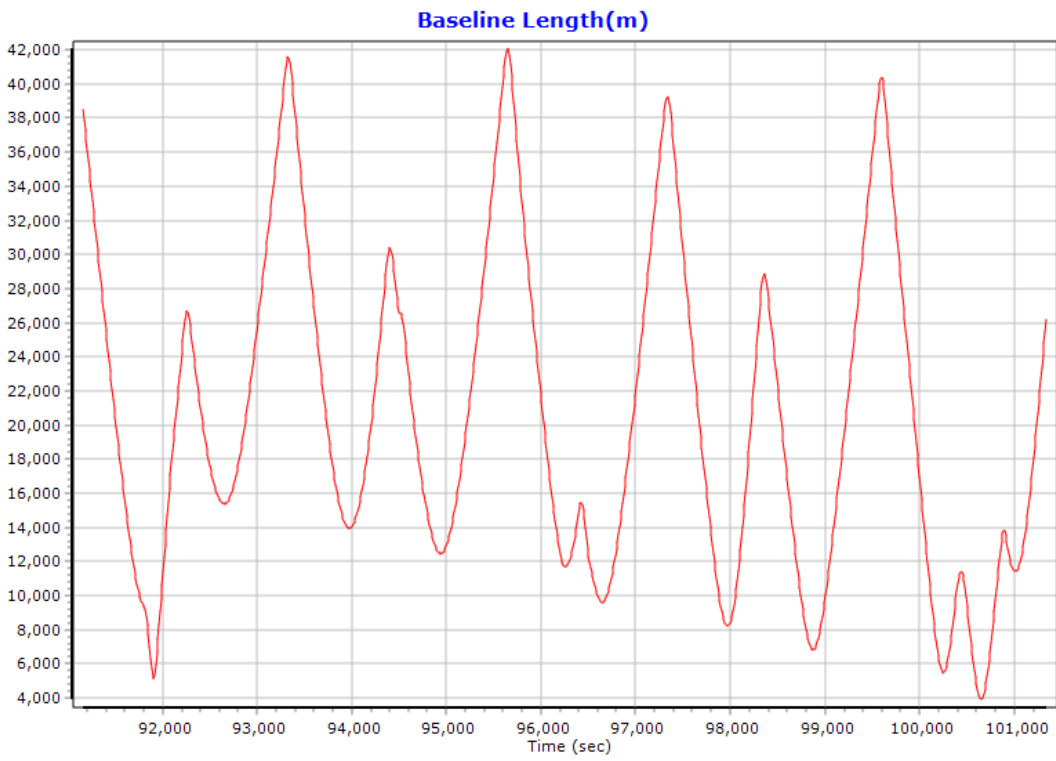
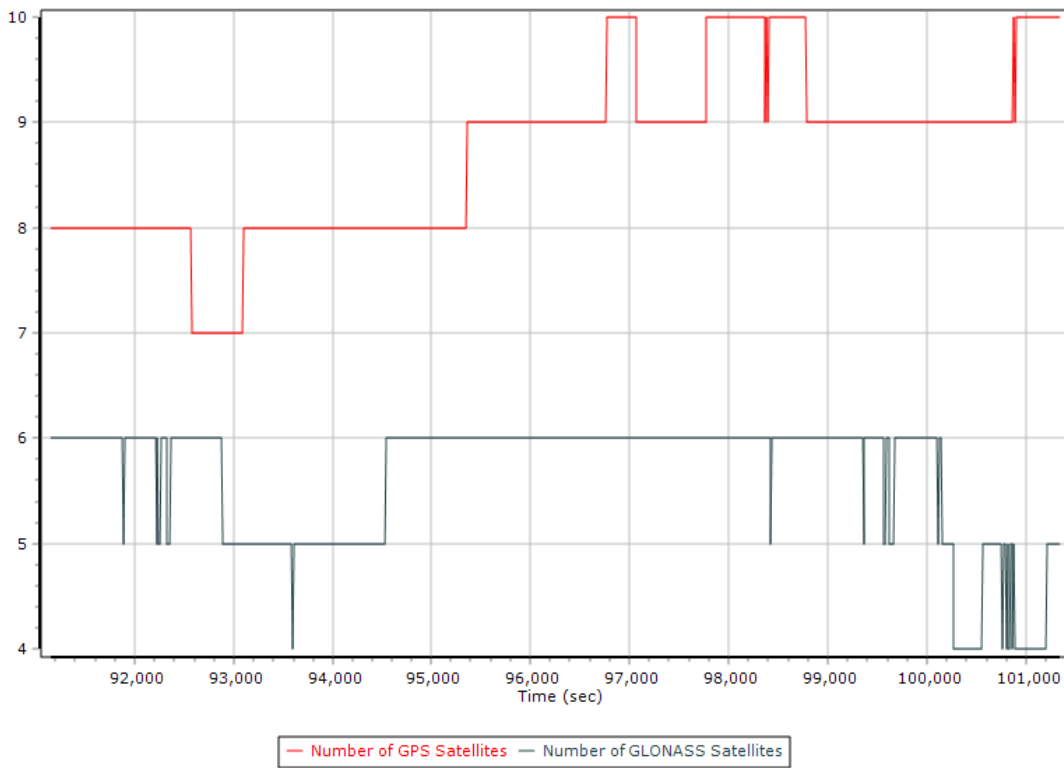




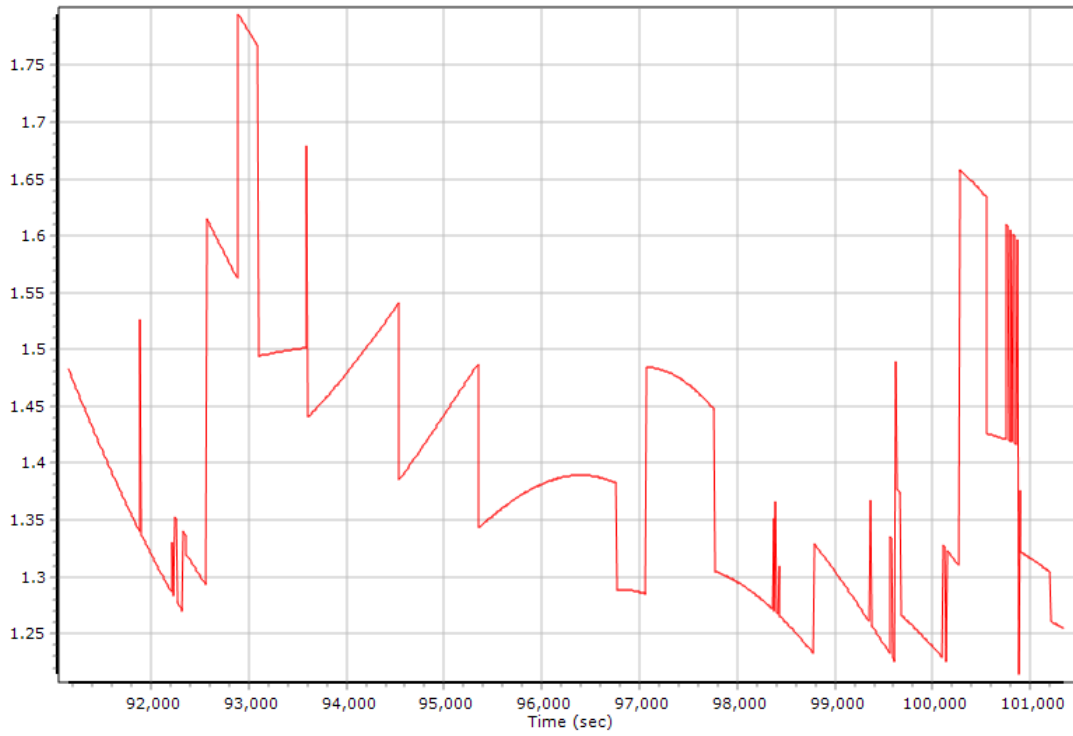




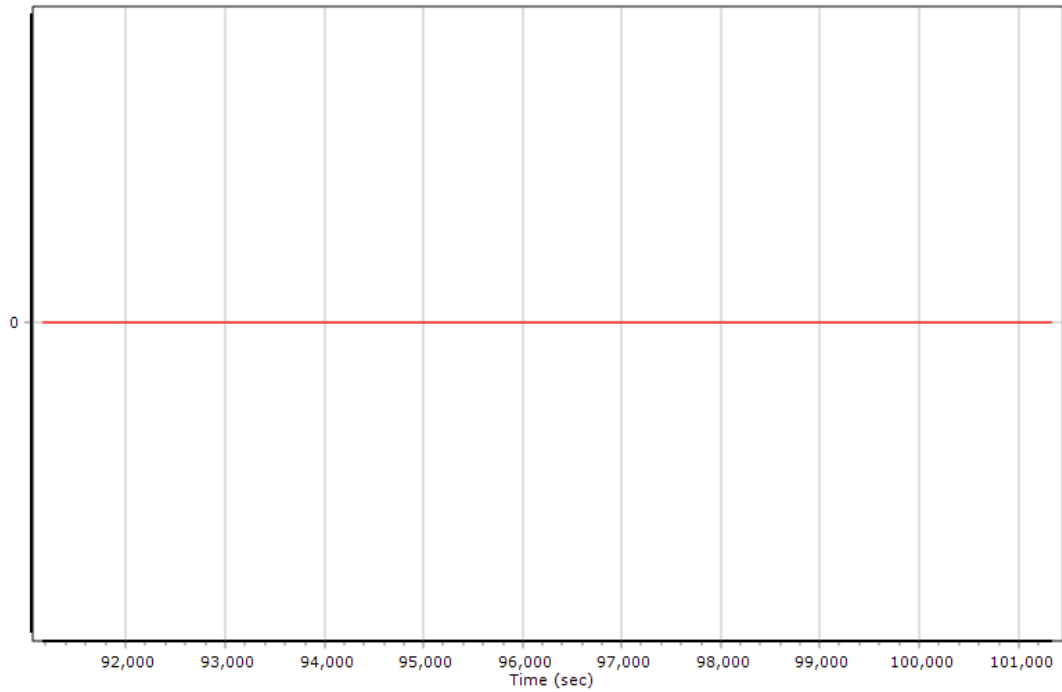




PDOP

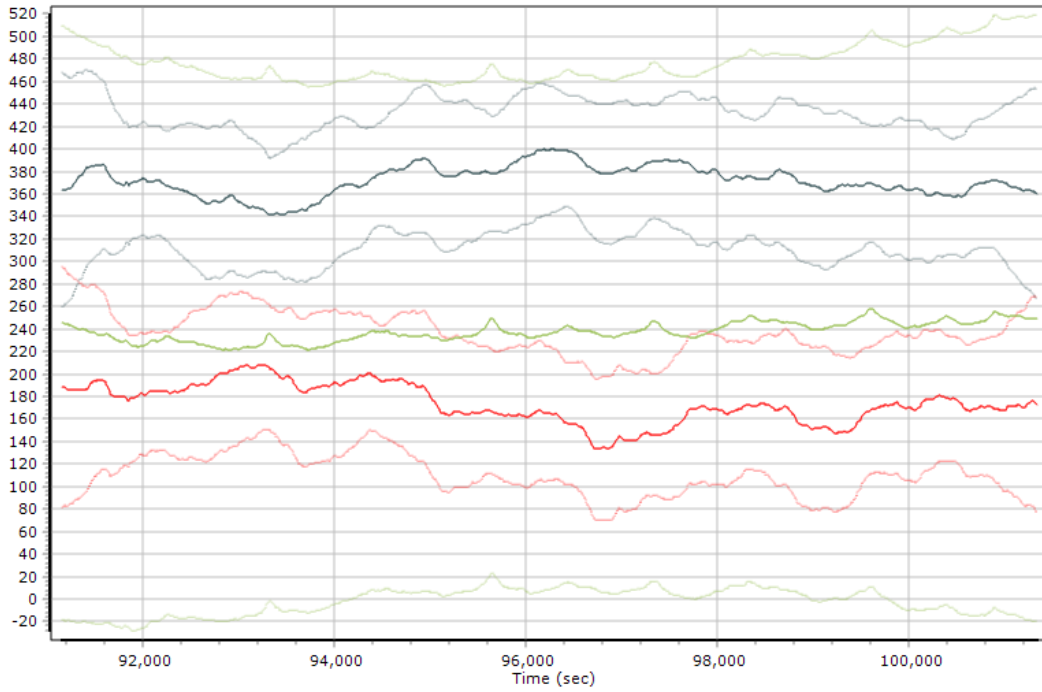


Processing Mode

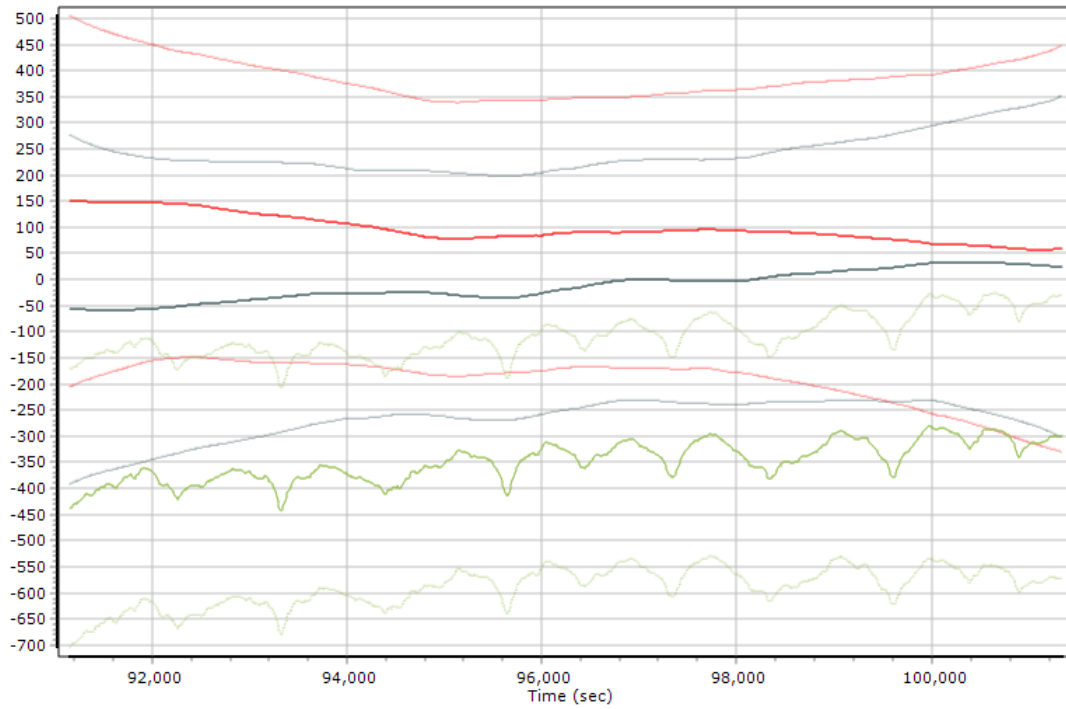


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

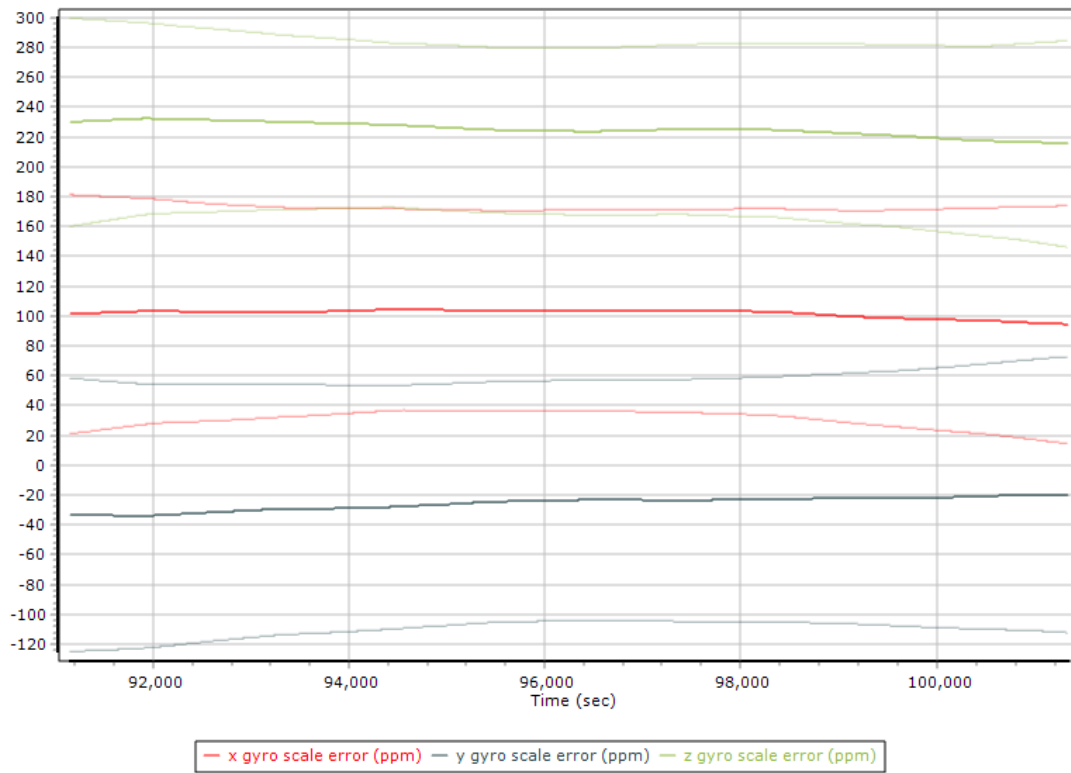
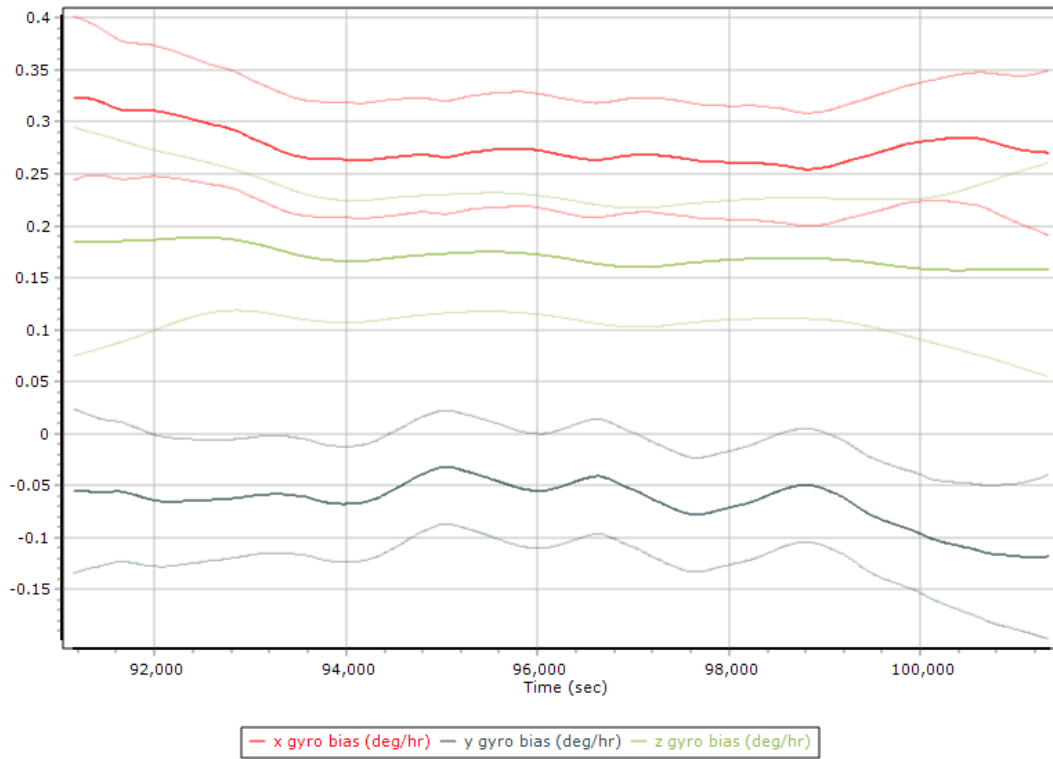
Sensor Errors



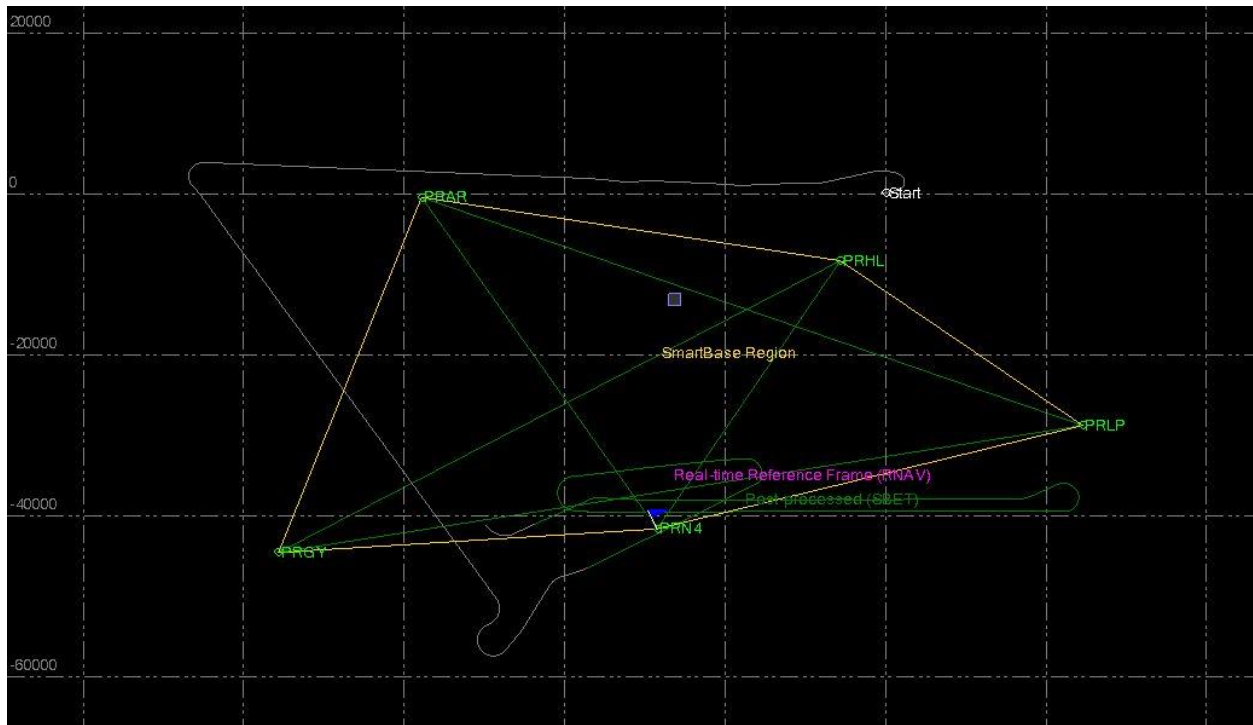
— x accelerometer bias (micro-g) — y accelerometer bias (micro-g) — z accelerometer bias (micro-g)



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



XXS19106A



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: 0.000 m	X: 0.000 deg
Y: 0.000 m	Y: 0.000 deg
Z: 0.000 m	Z: 0.000 deg

Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: 0.039 m	X: 0.000 deg
Y: 0.120 m	Y: 0.000 deg
Z: -0.777 m	Z: 0.000 deg

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

OK Cancel

Project Settings

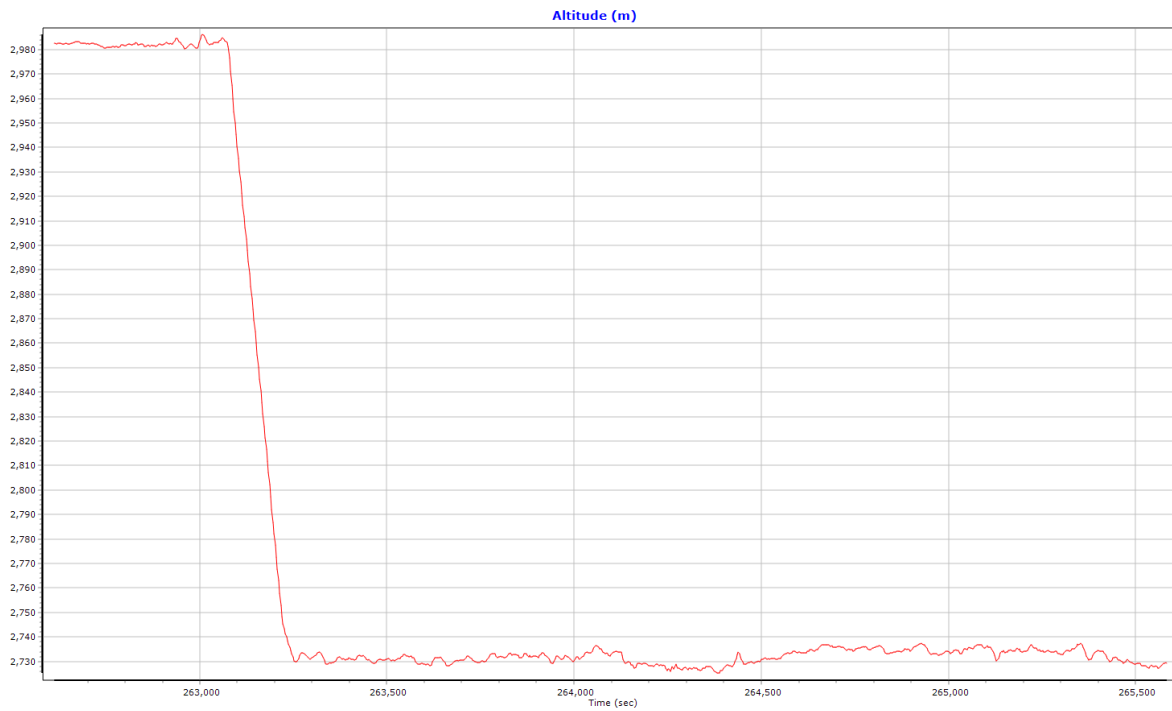
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
Timing
Algorithms
Initialization
Lever Arms and Mounting Angles
Export
Camera
LIDAR
SAR

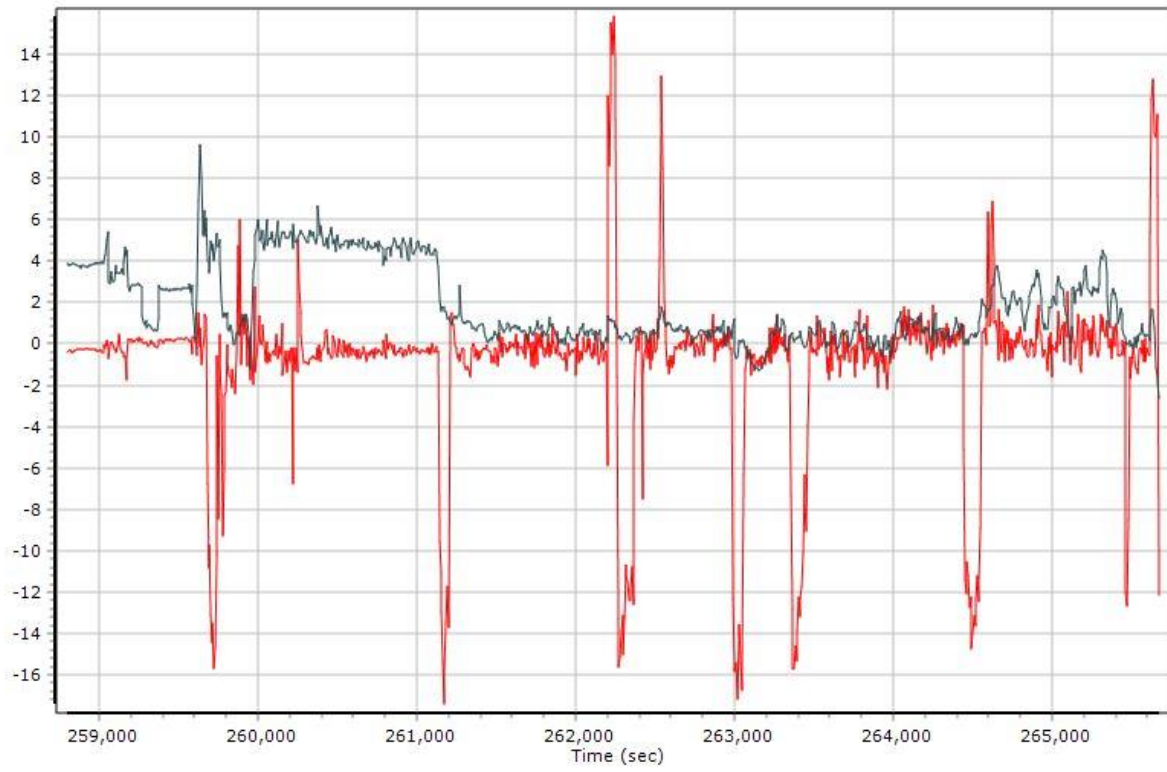
Timing

Start: 262609.419
End: 265584.101
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

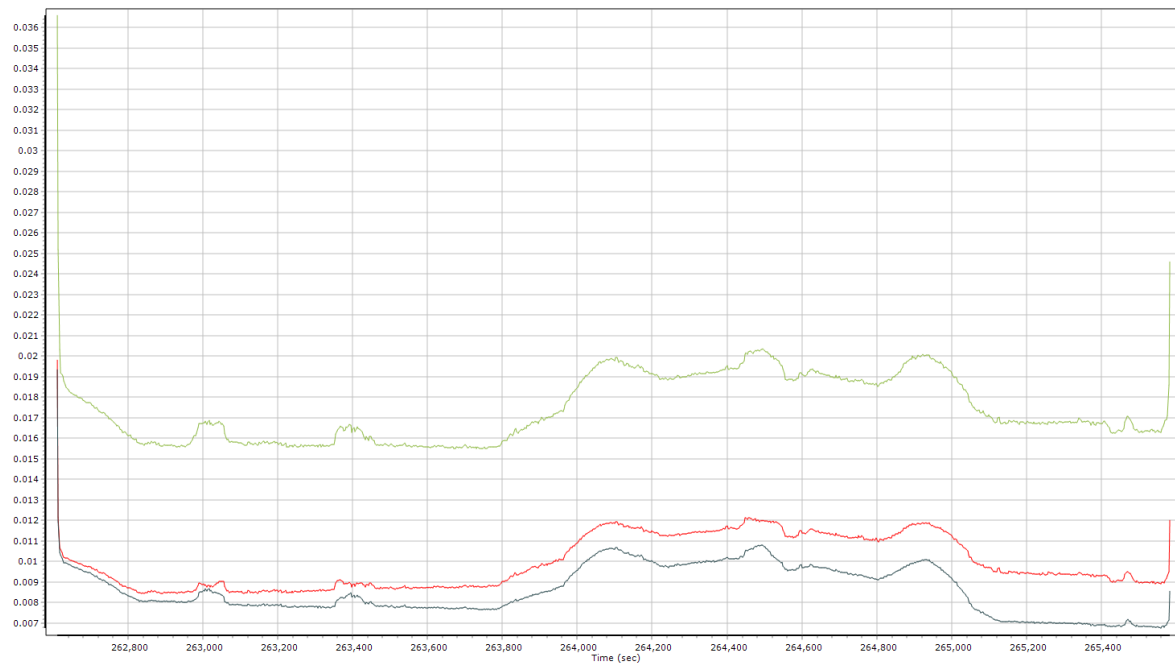
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel

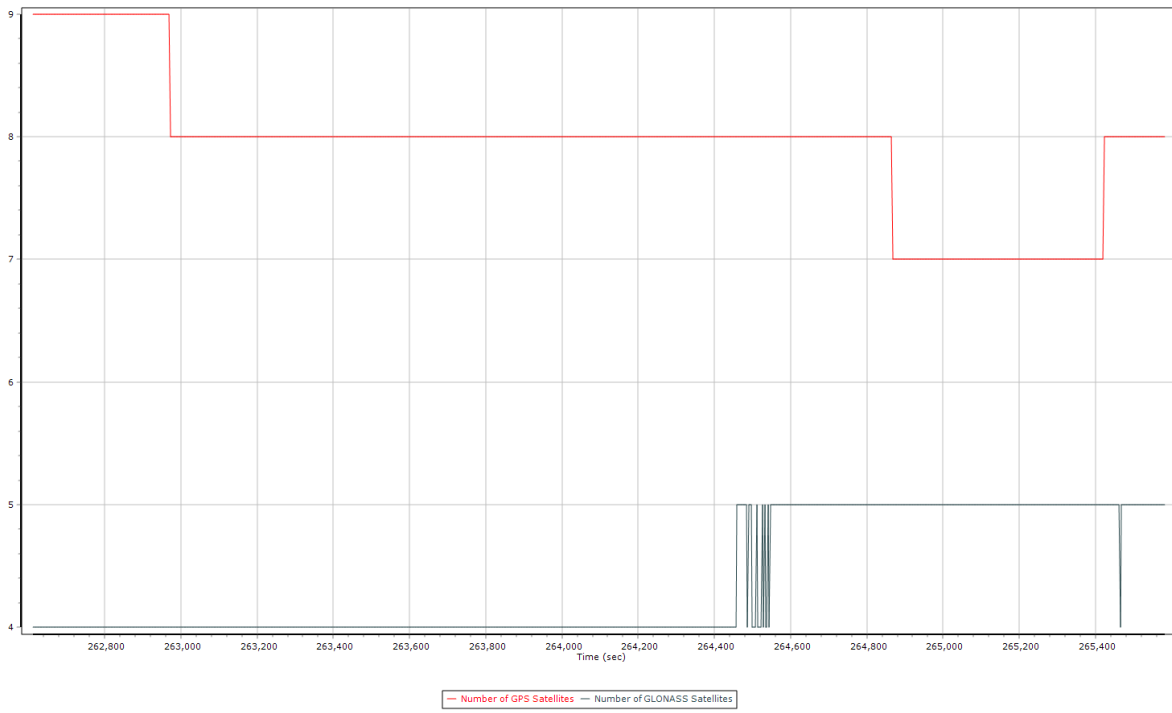
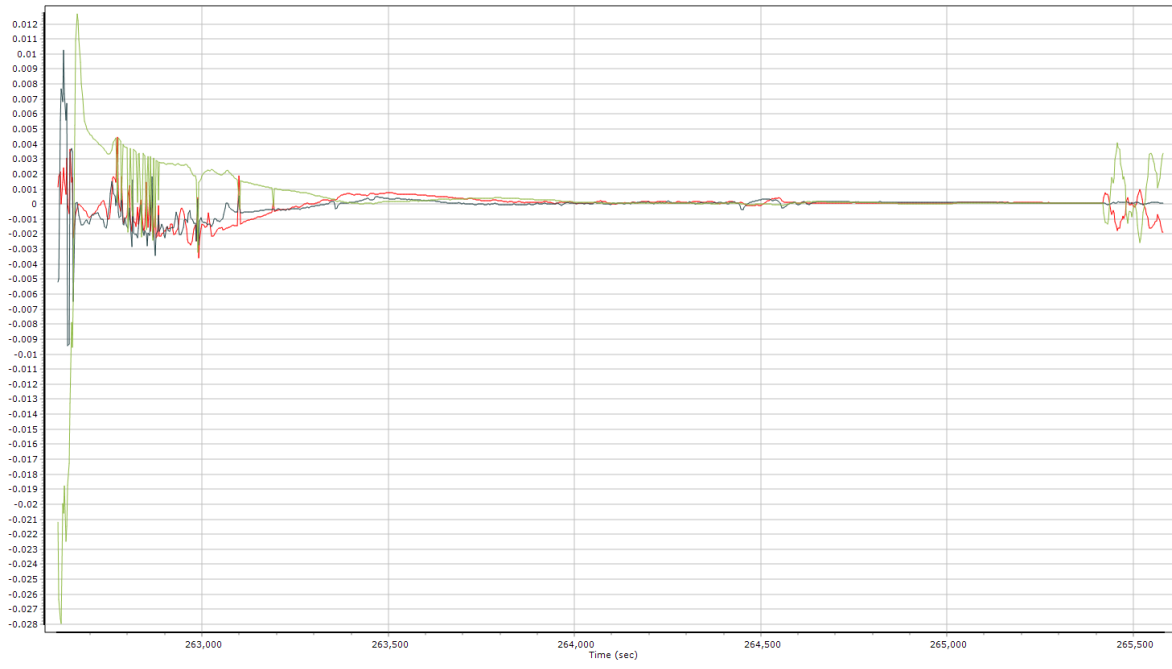


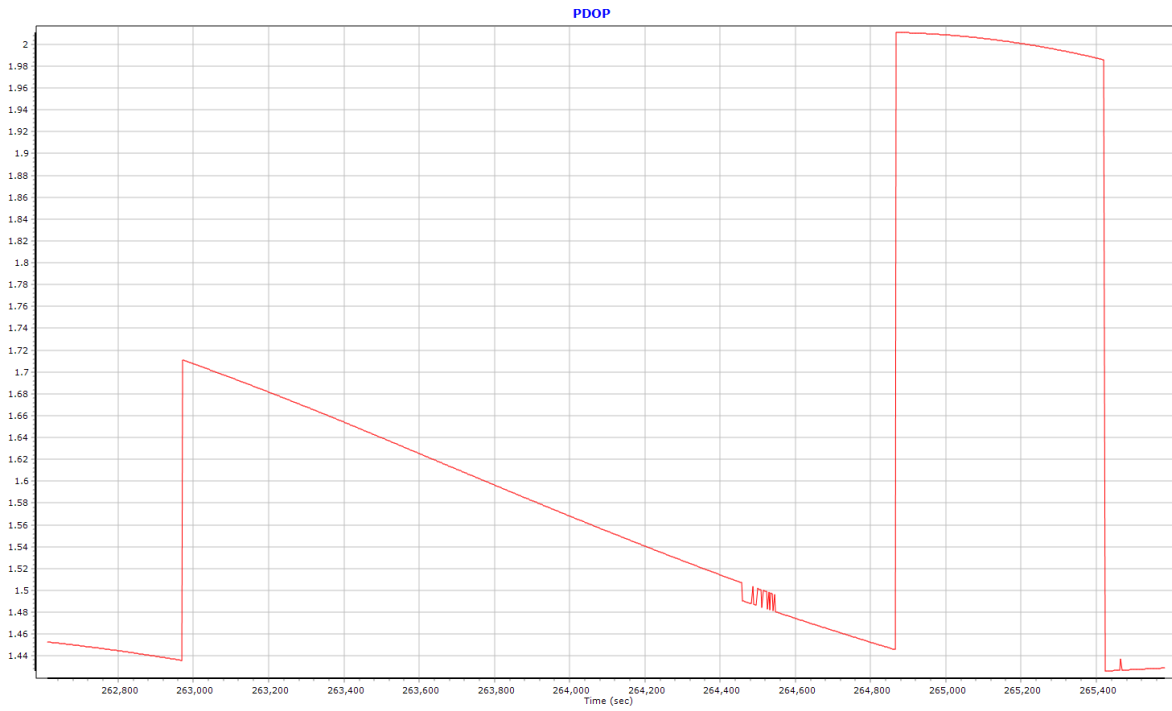
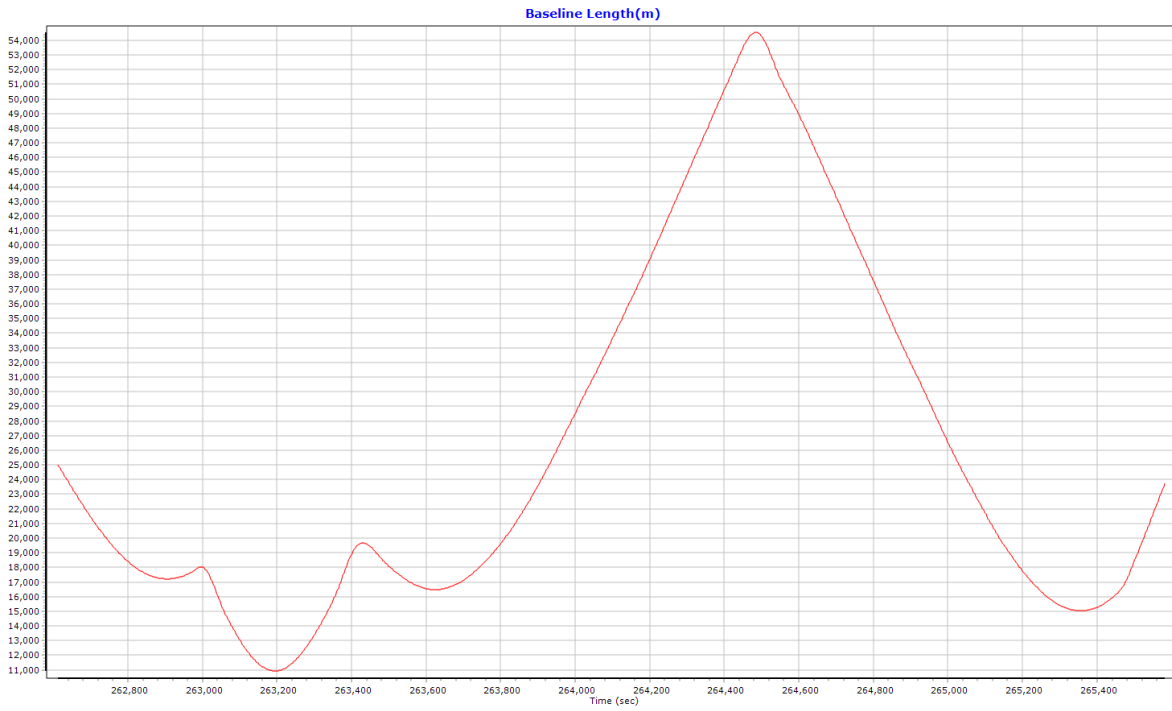


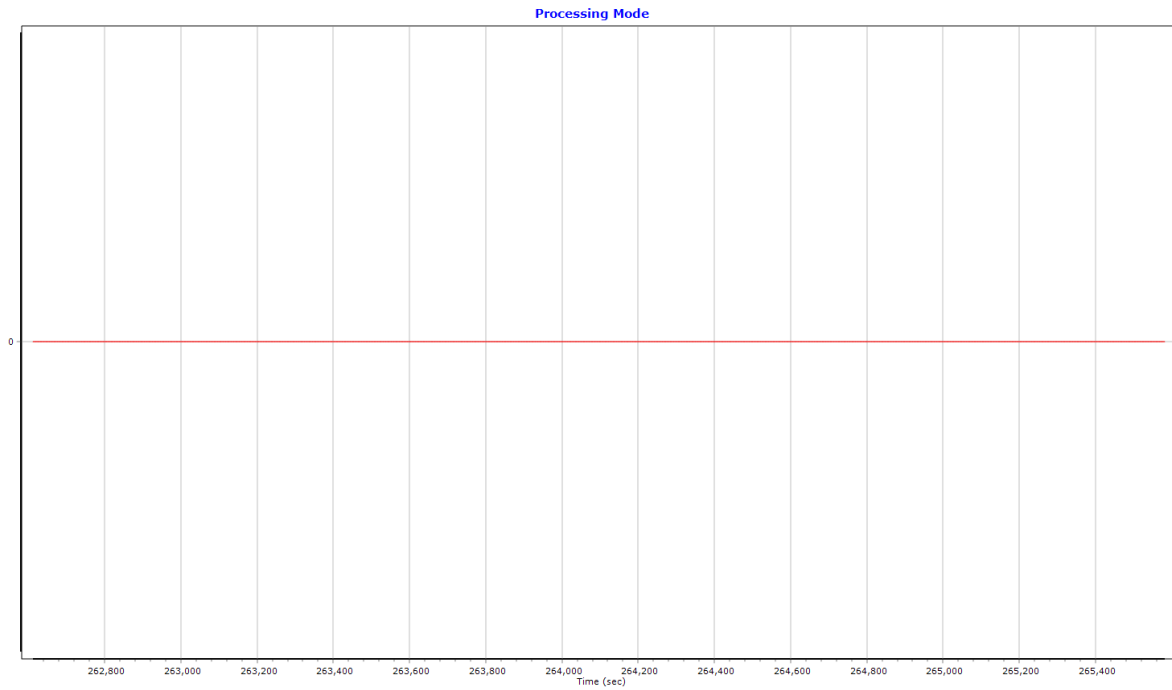
— Roll (deg) — Pitch (deg)



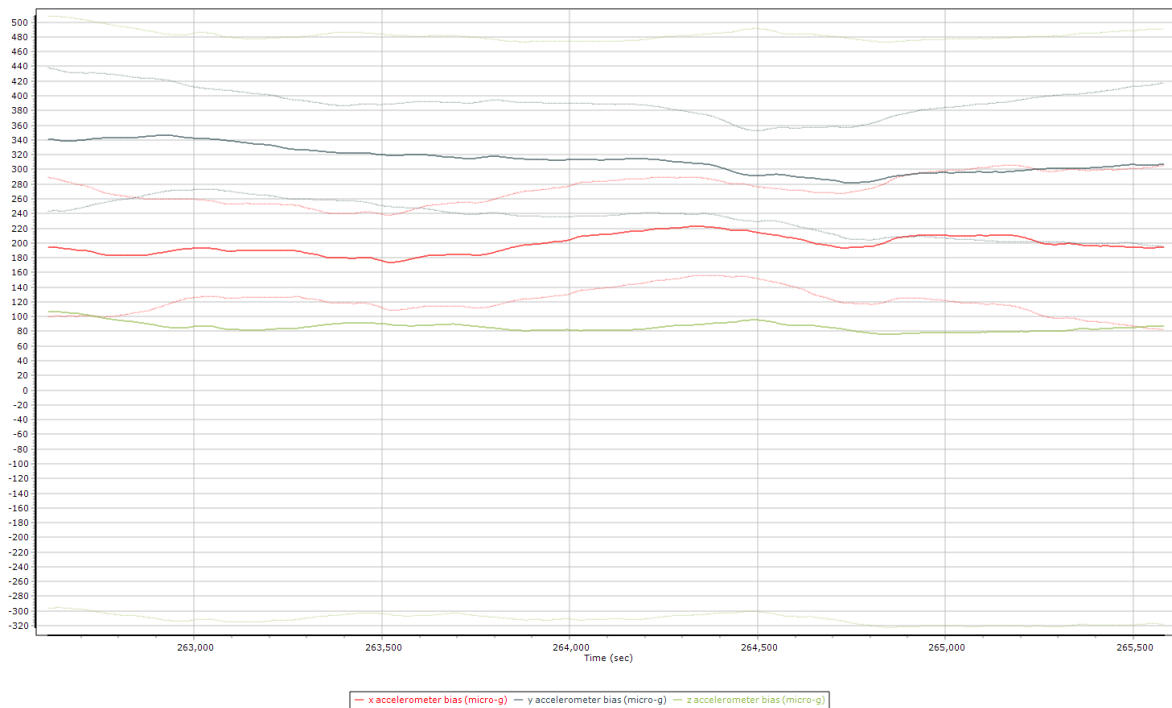
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)

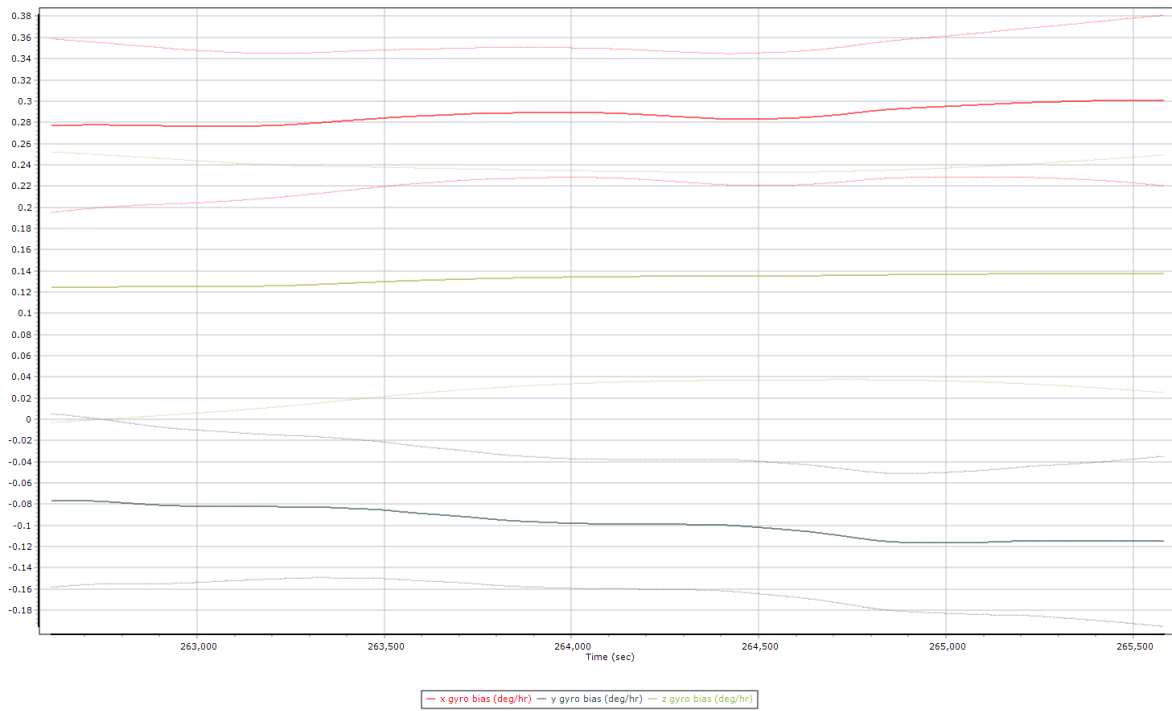
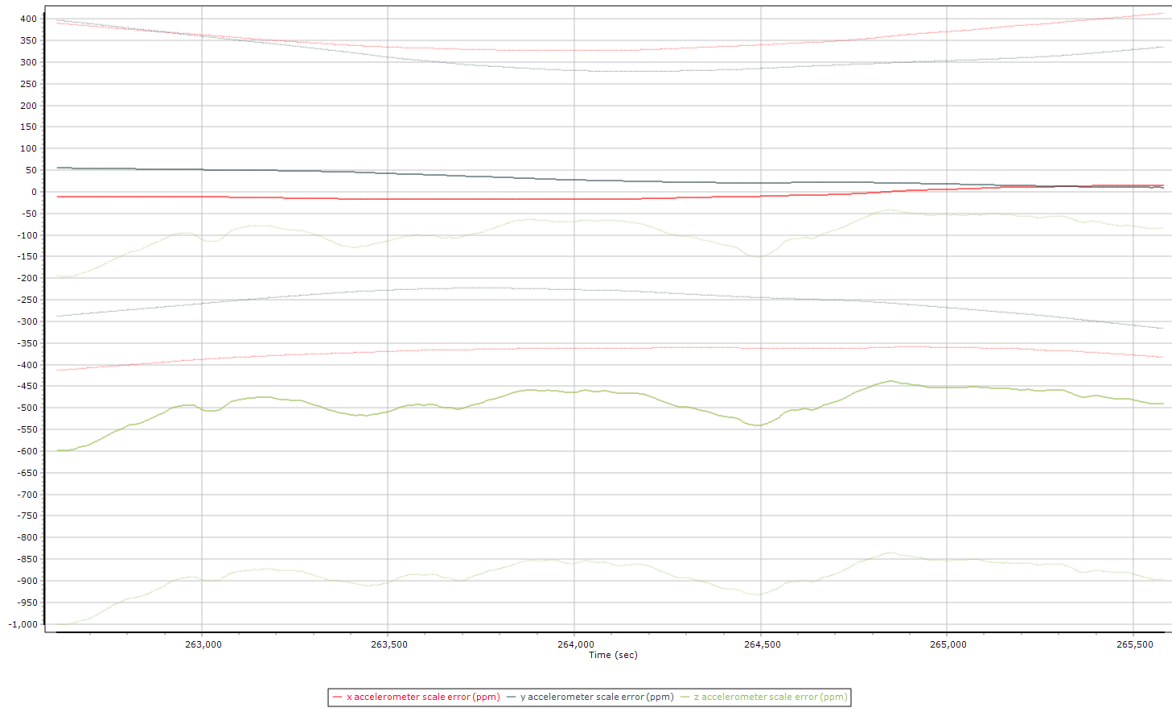


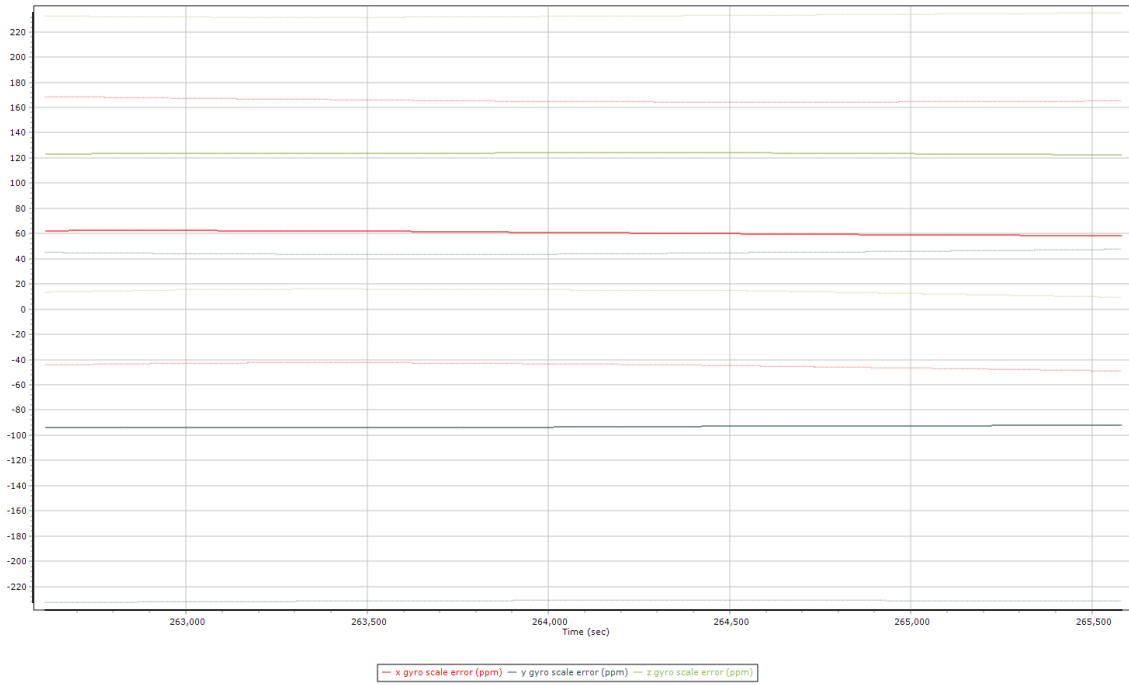




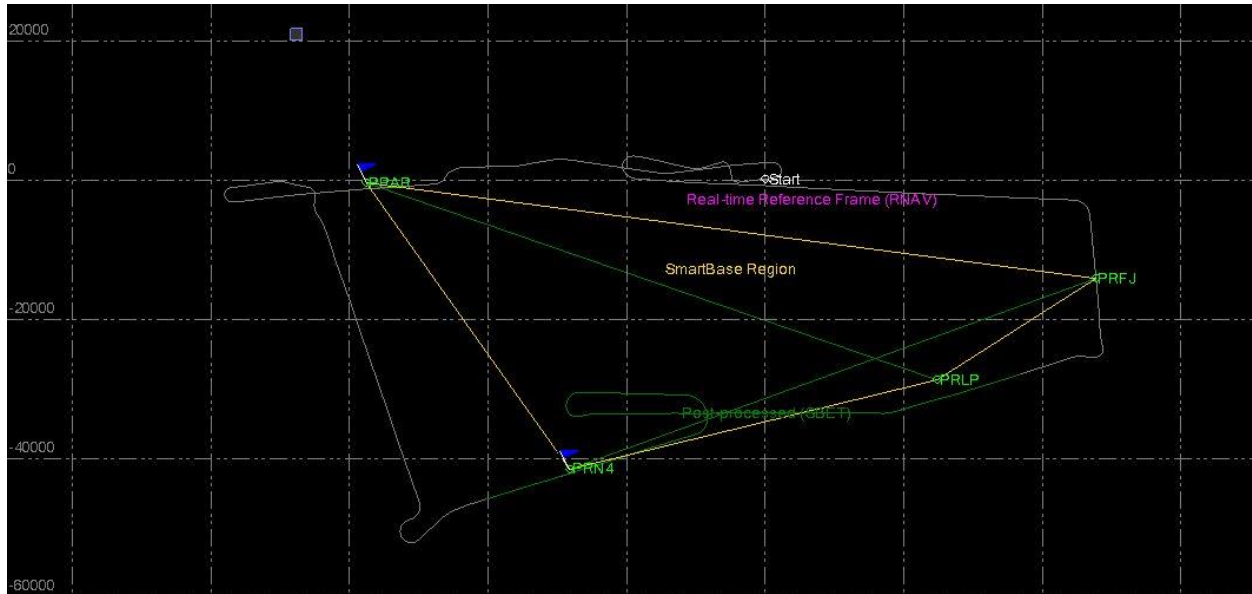
Sensor Errors

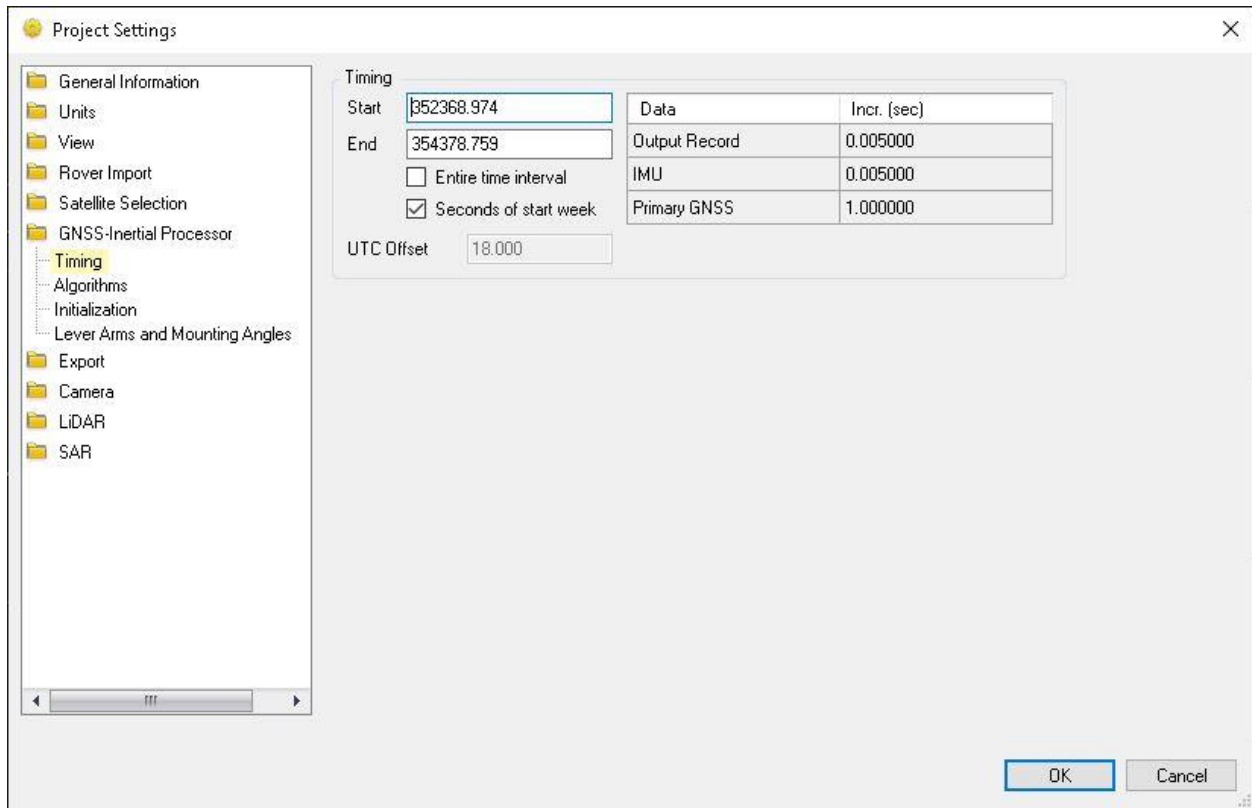
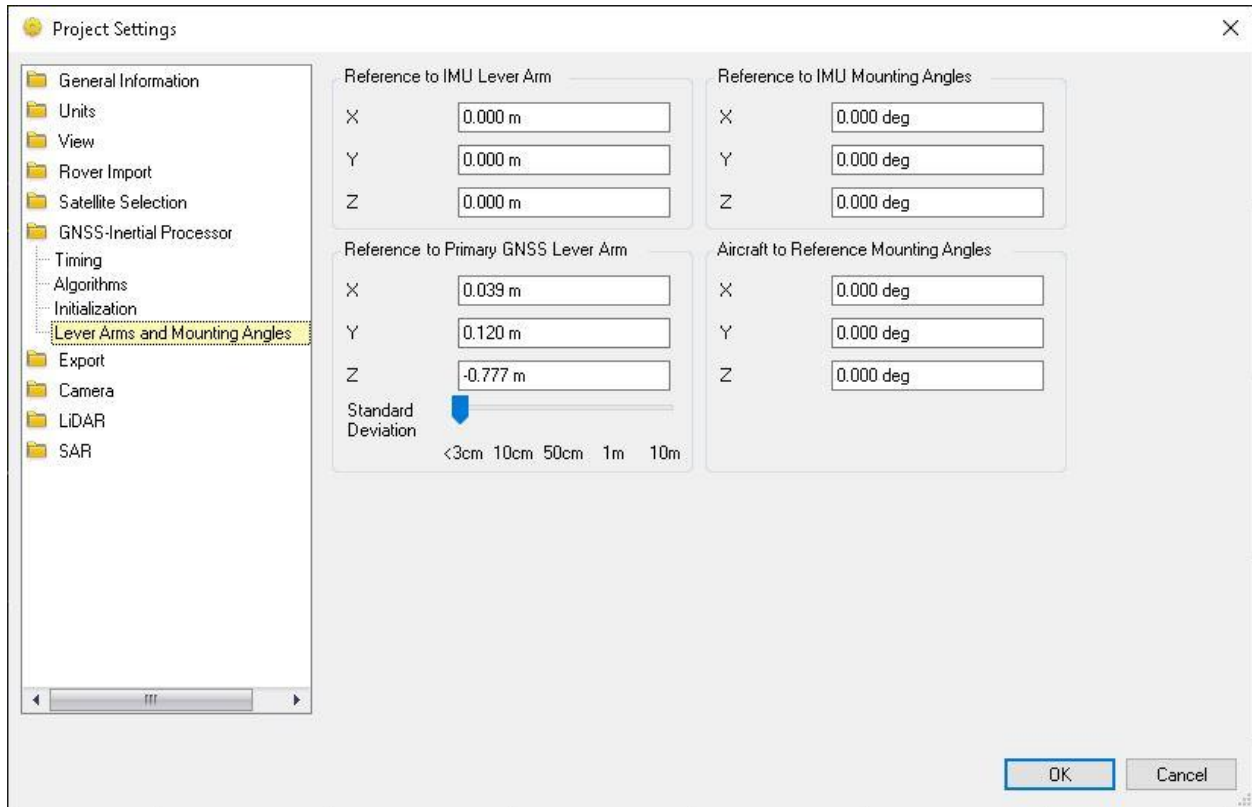


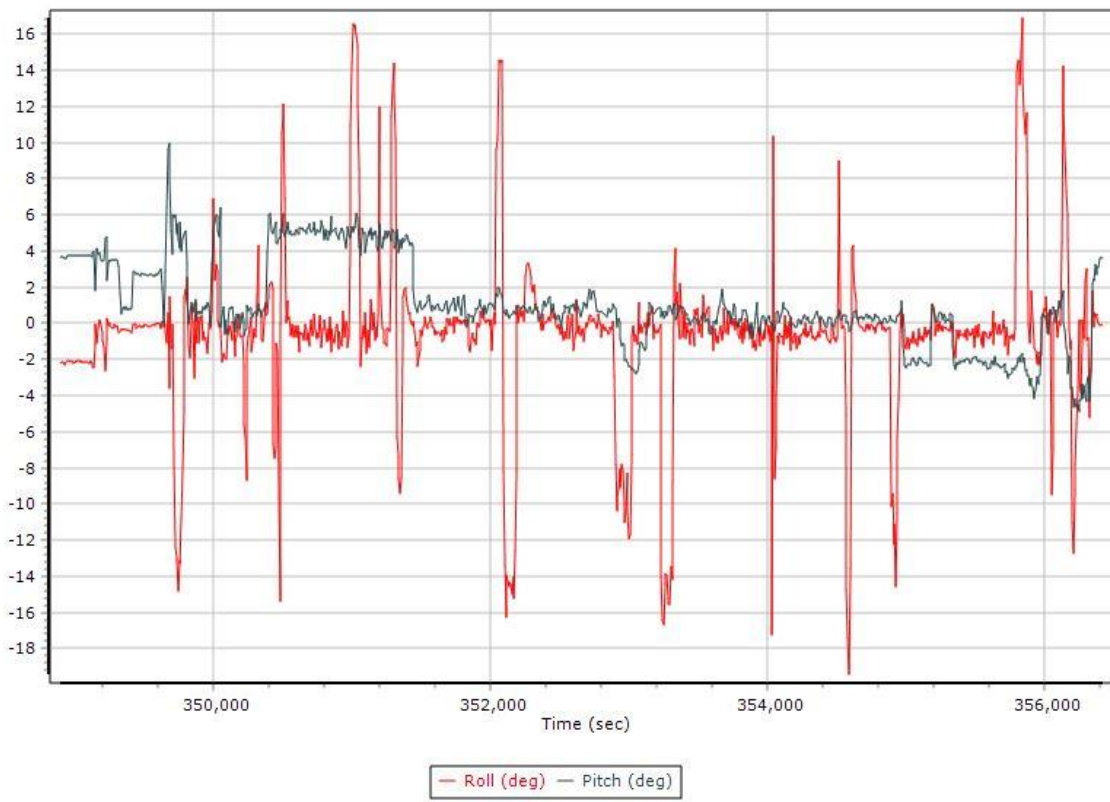
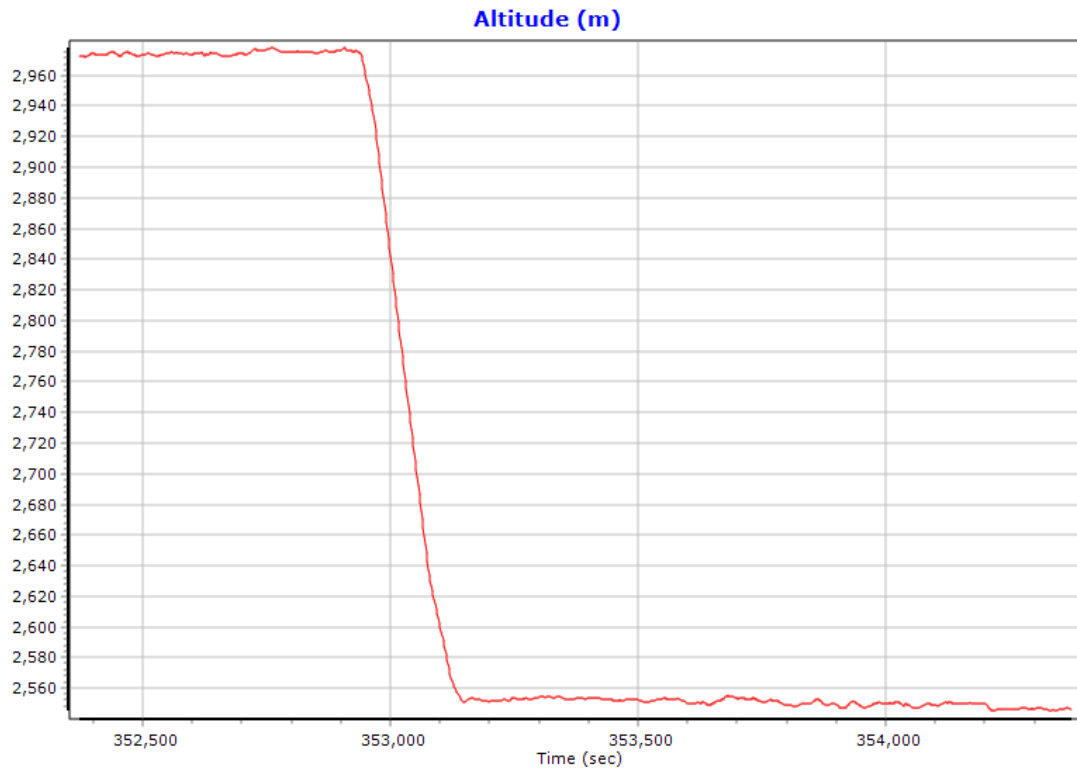


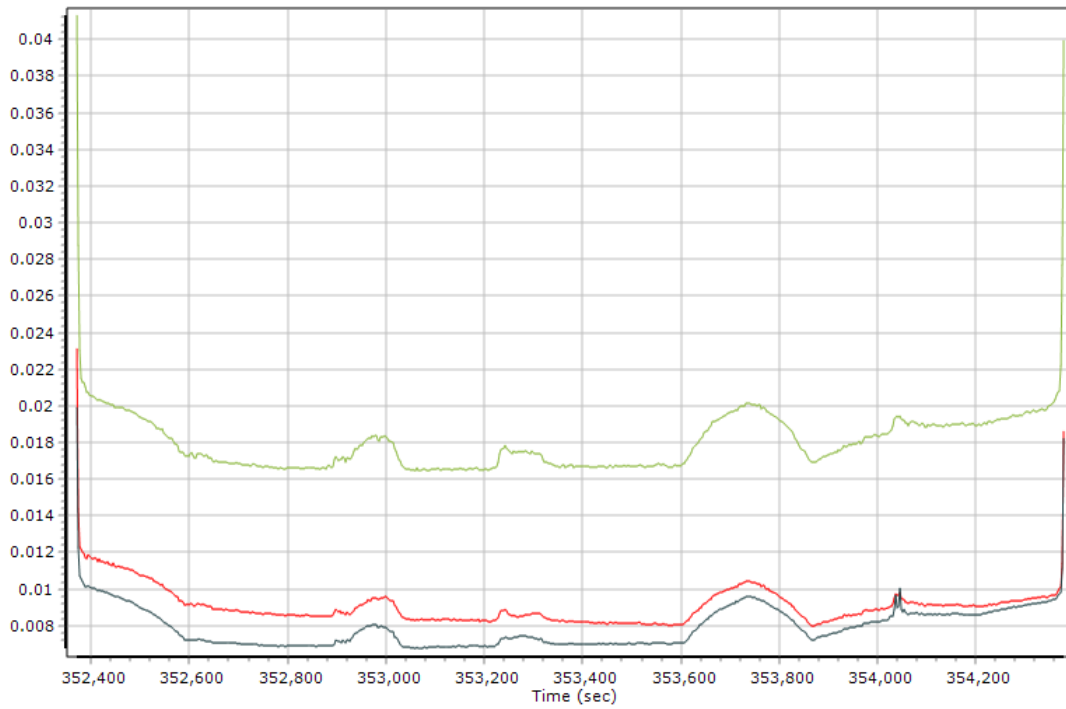


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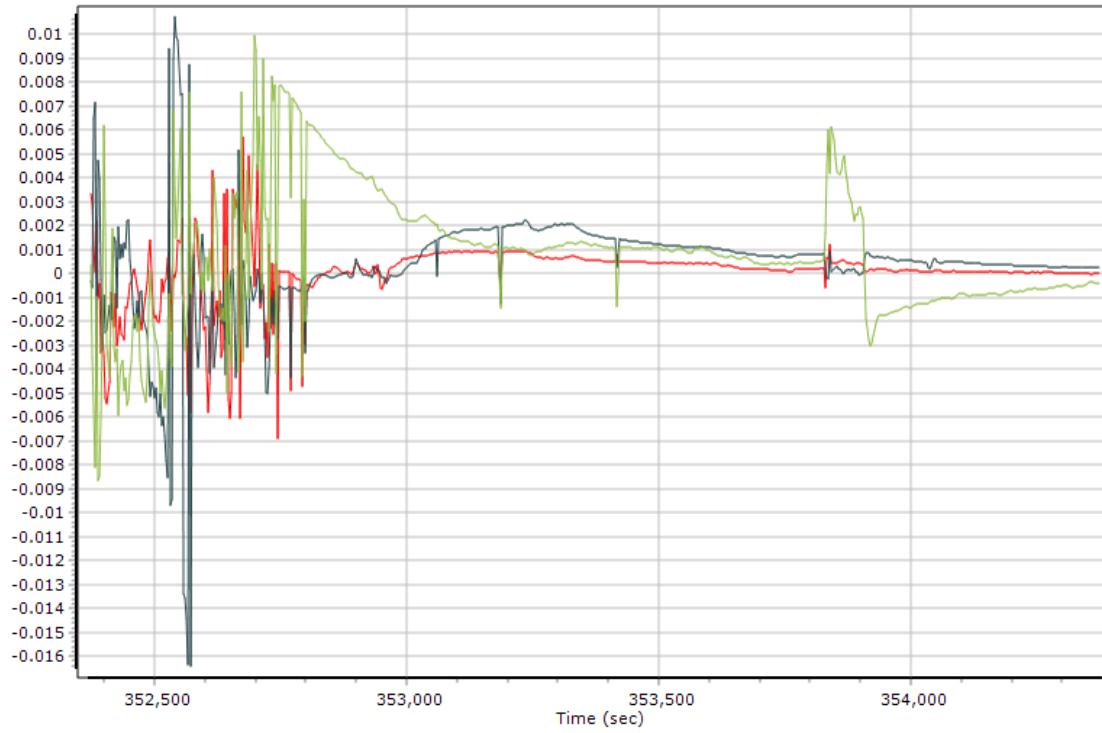




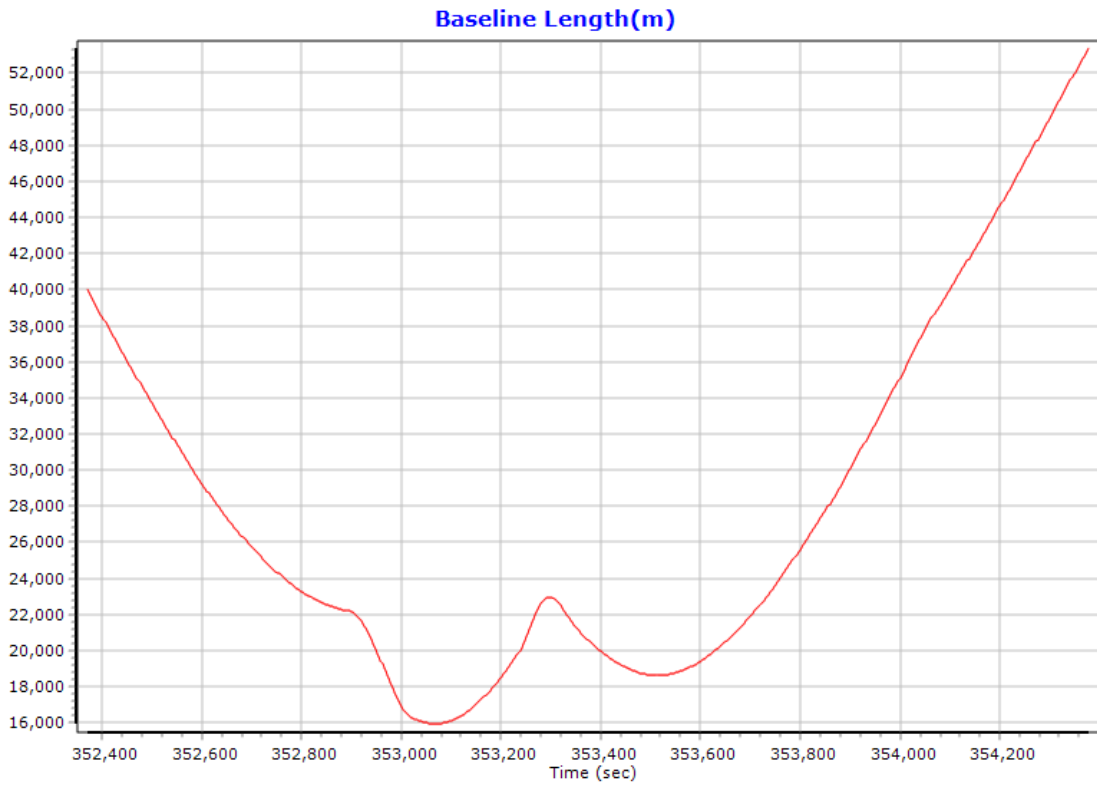
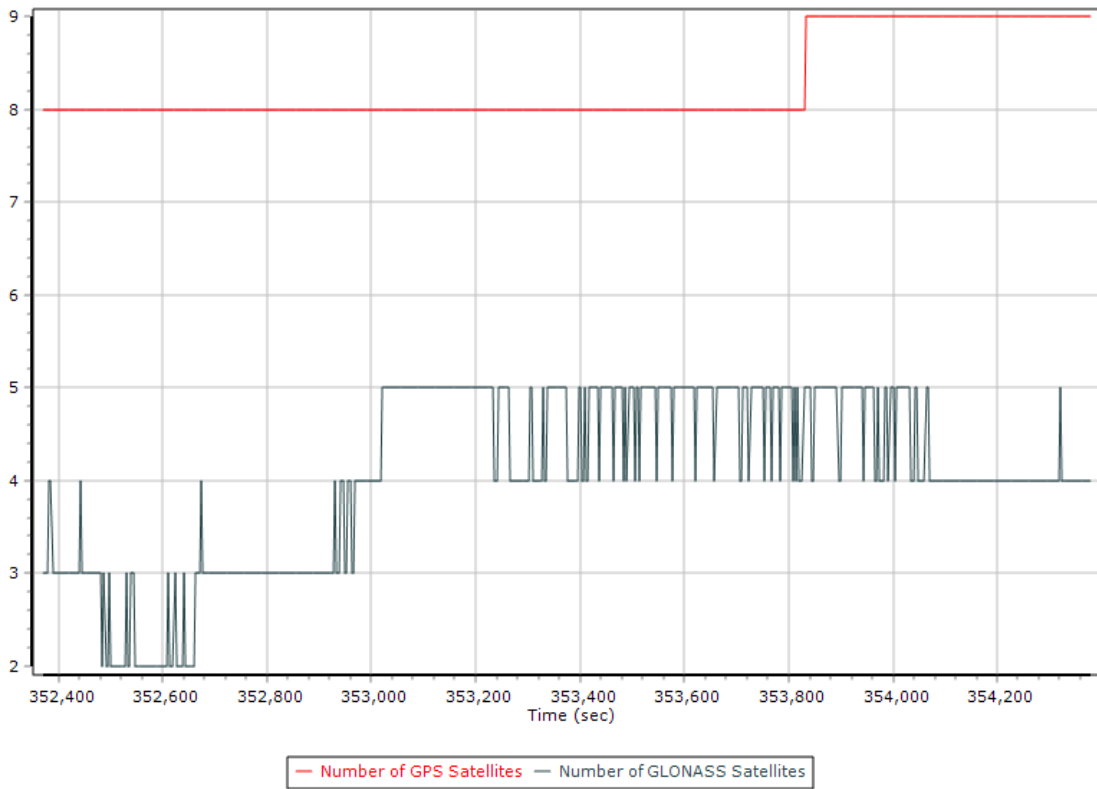




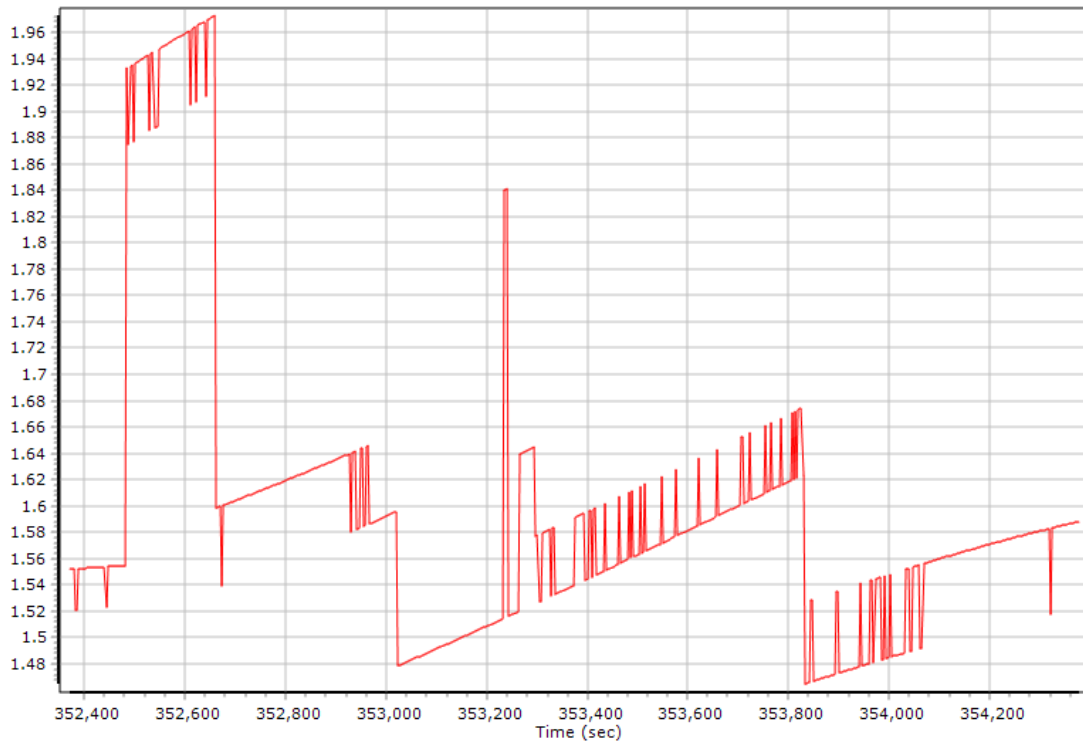
— North Position Error RMS (m) — East Position Error RMS (m) — Down Position Error RMS (m)



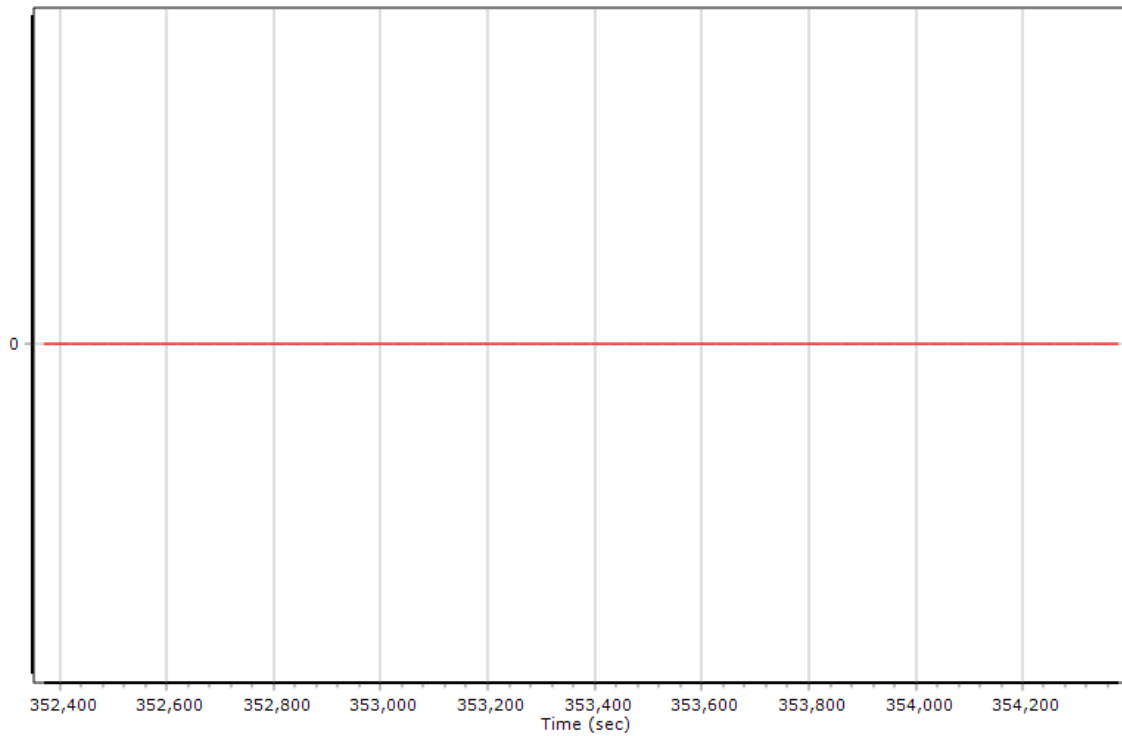
— North (m) — East (m) — Down (m) — DR mode



PDOP

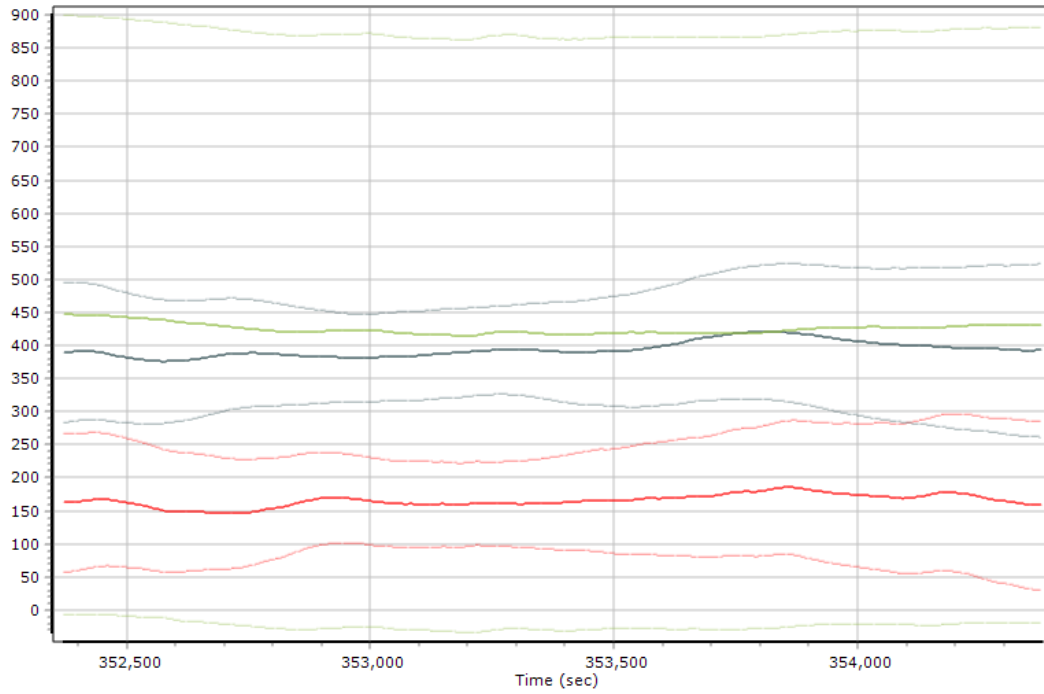


Processing Mode

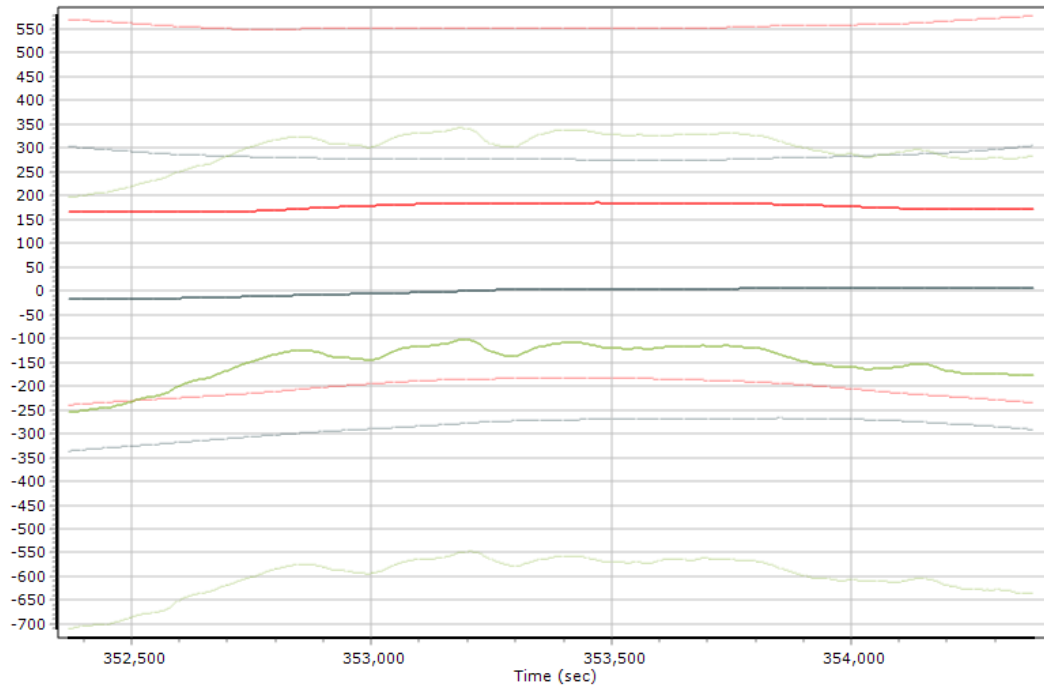


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

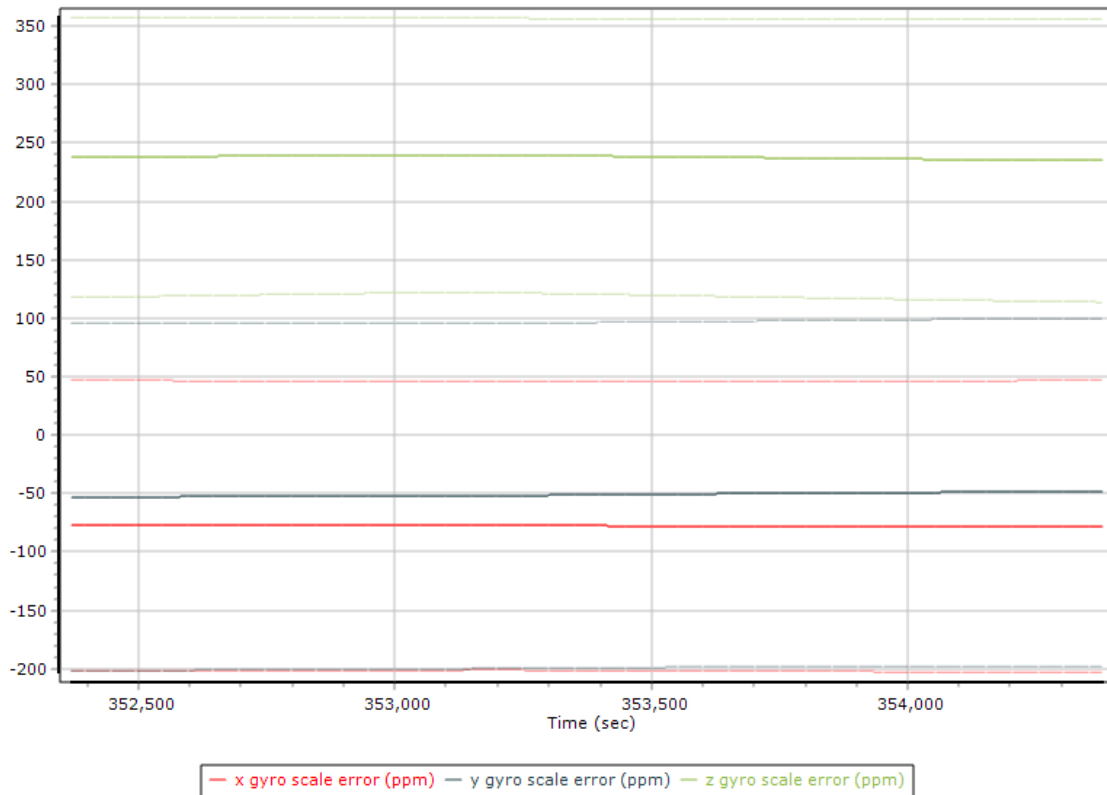
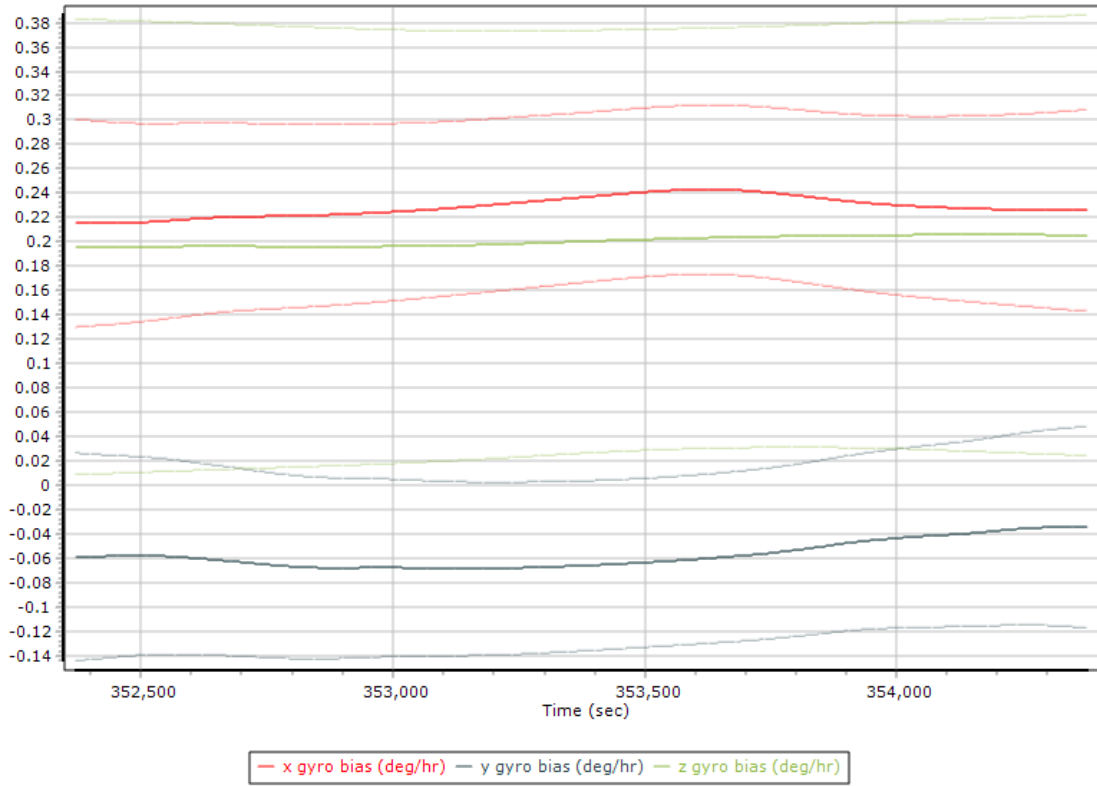
Sensor Errors



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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May 29 2019

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End