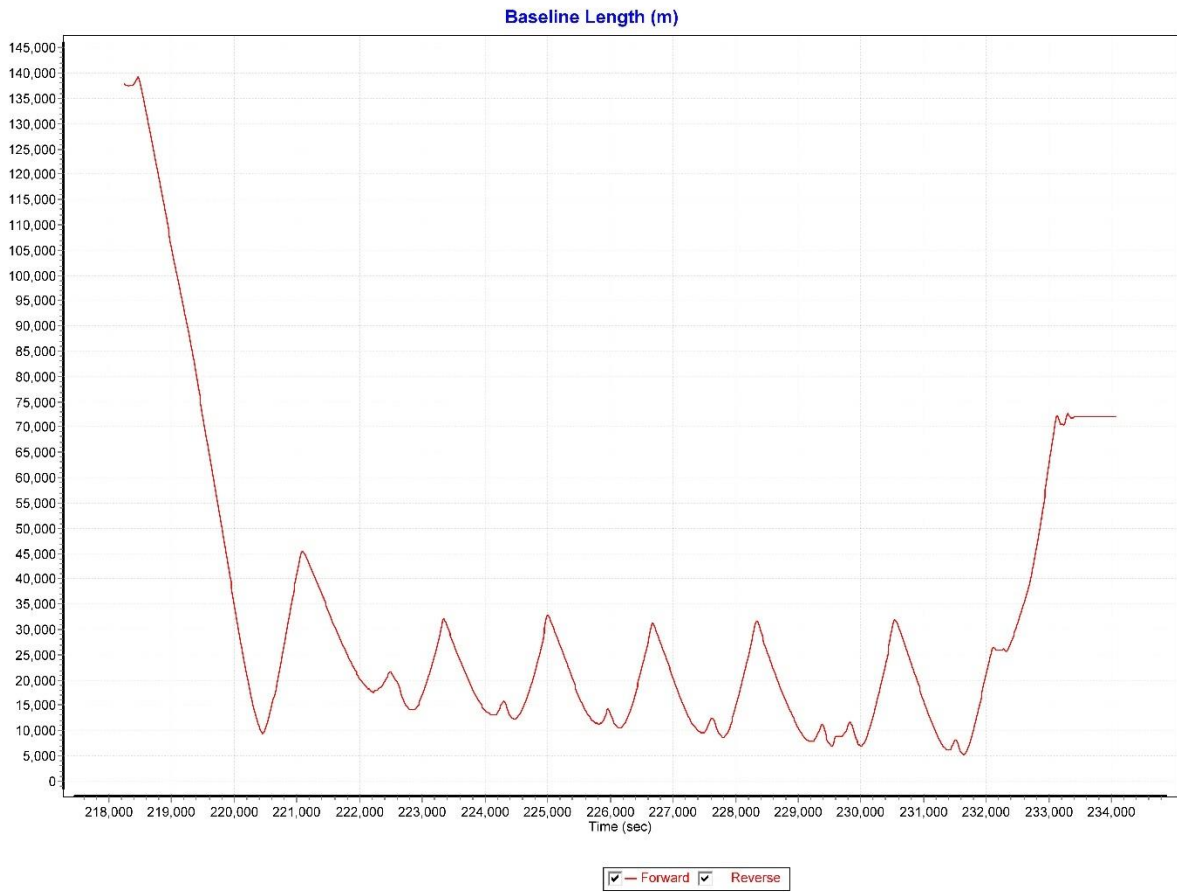


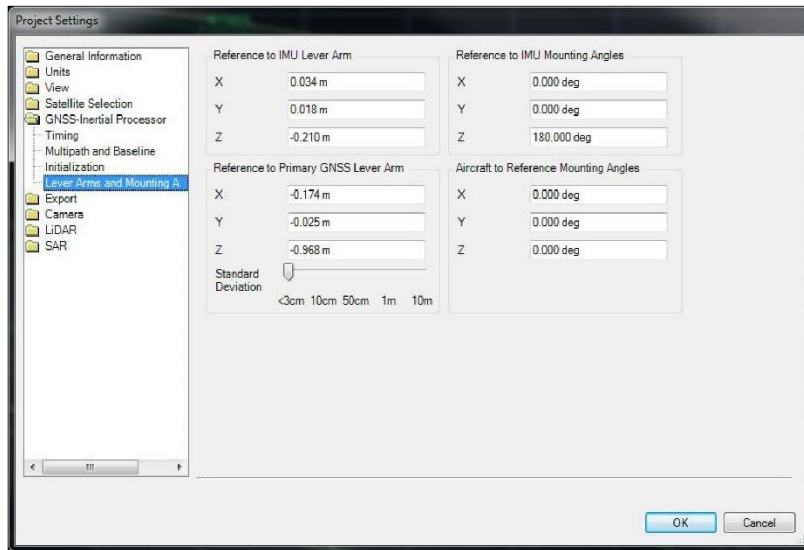
Appendix F: GPS Processing Blocks 9-13

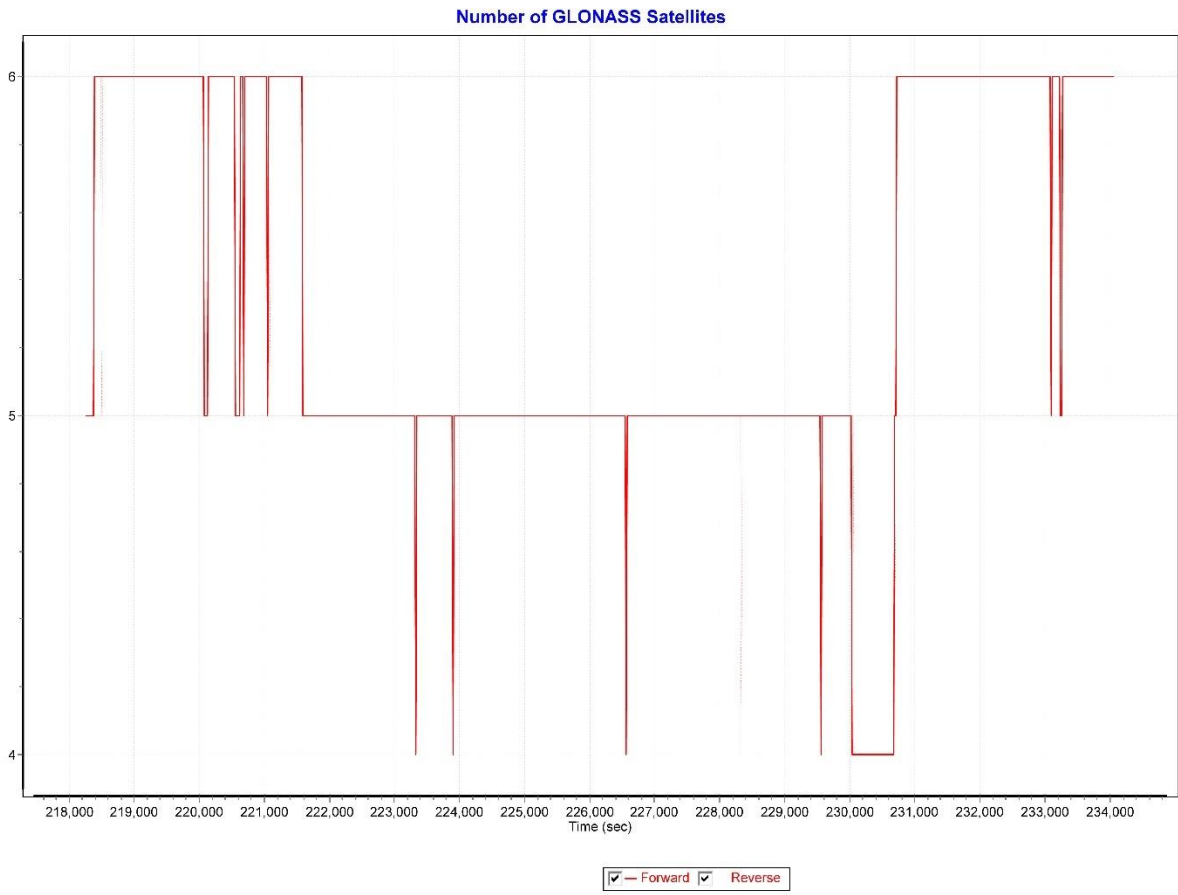
TRAJECTORY PLOTS BY FLIGHT

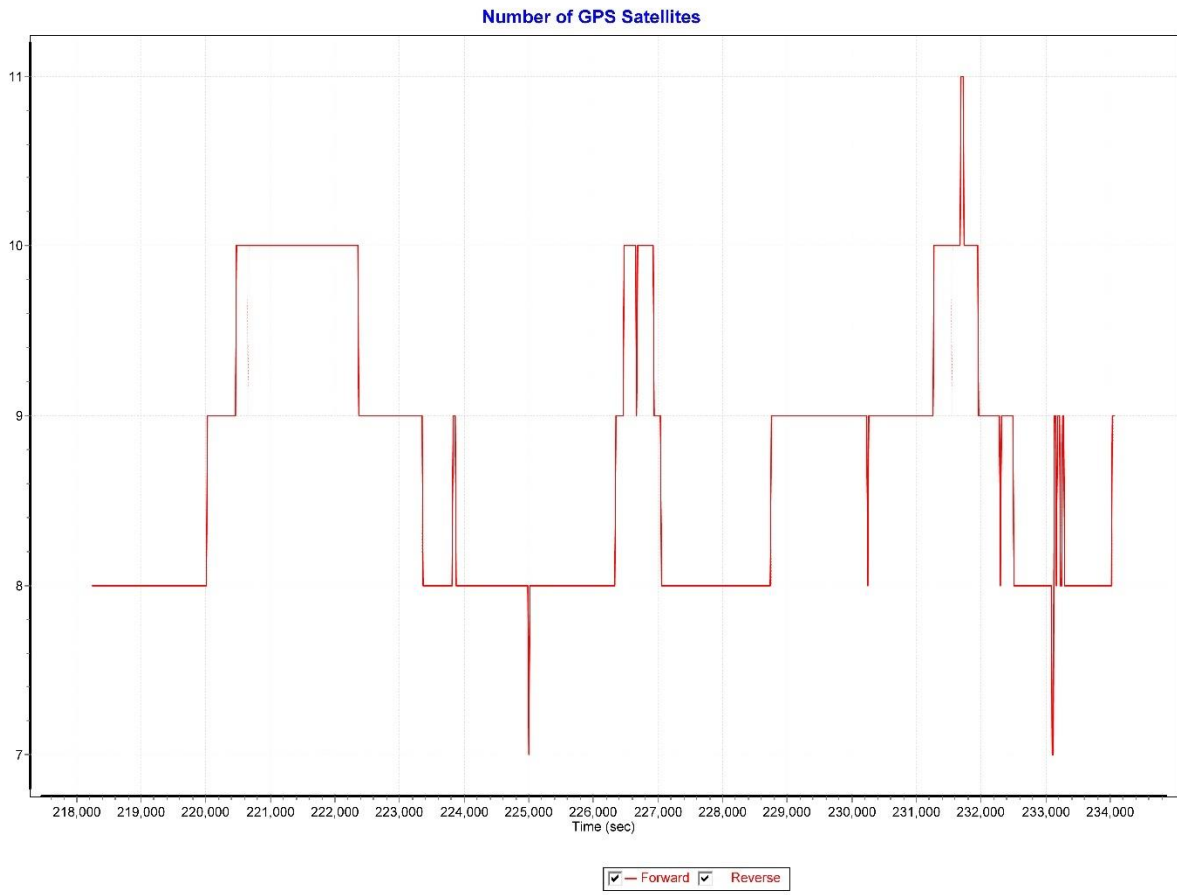
CAU18032A

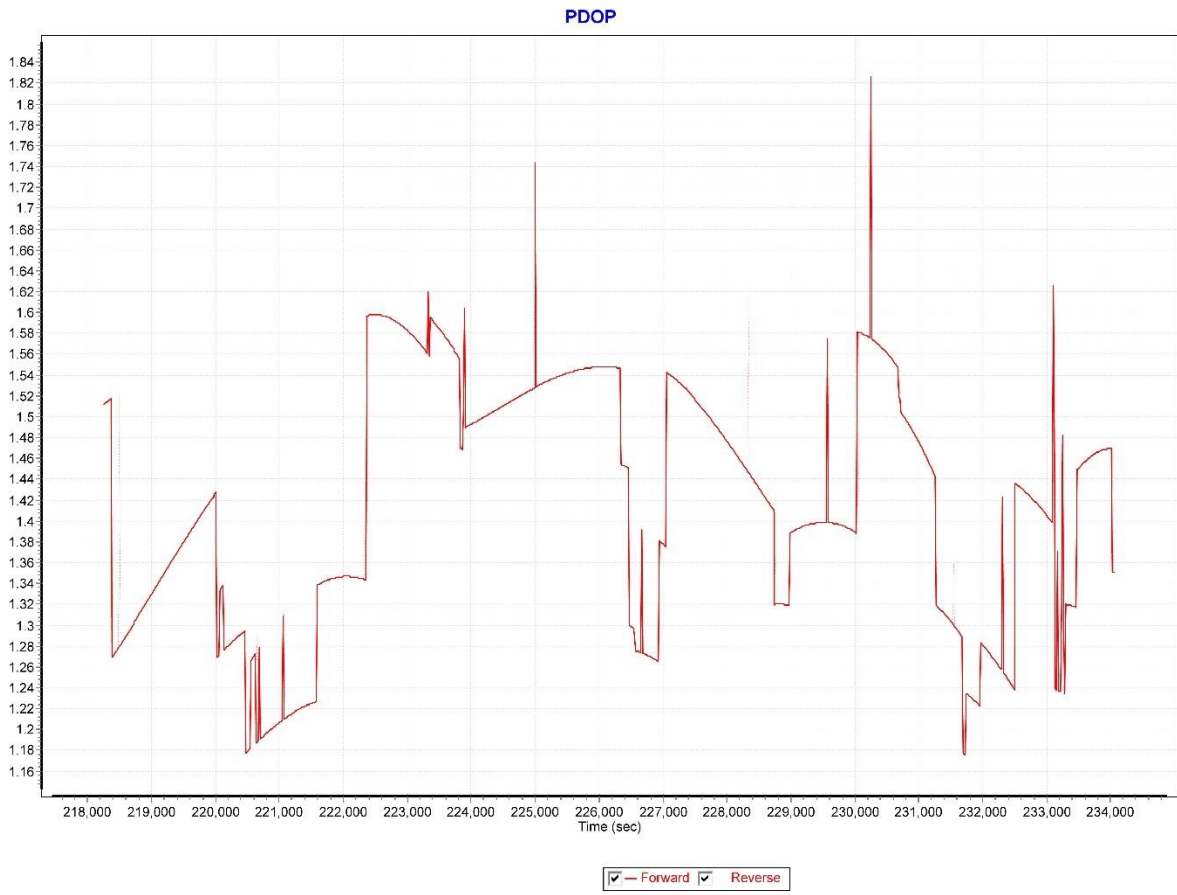




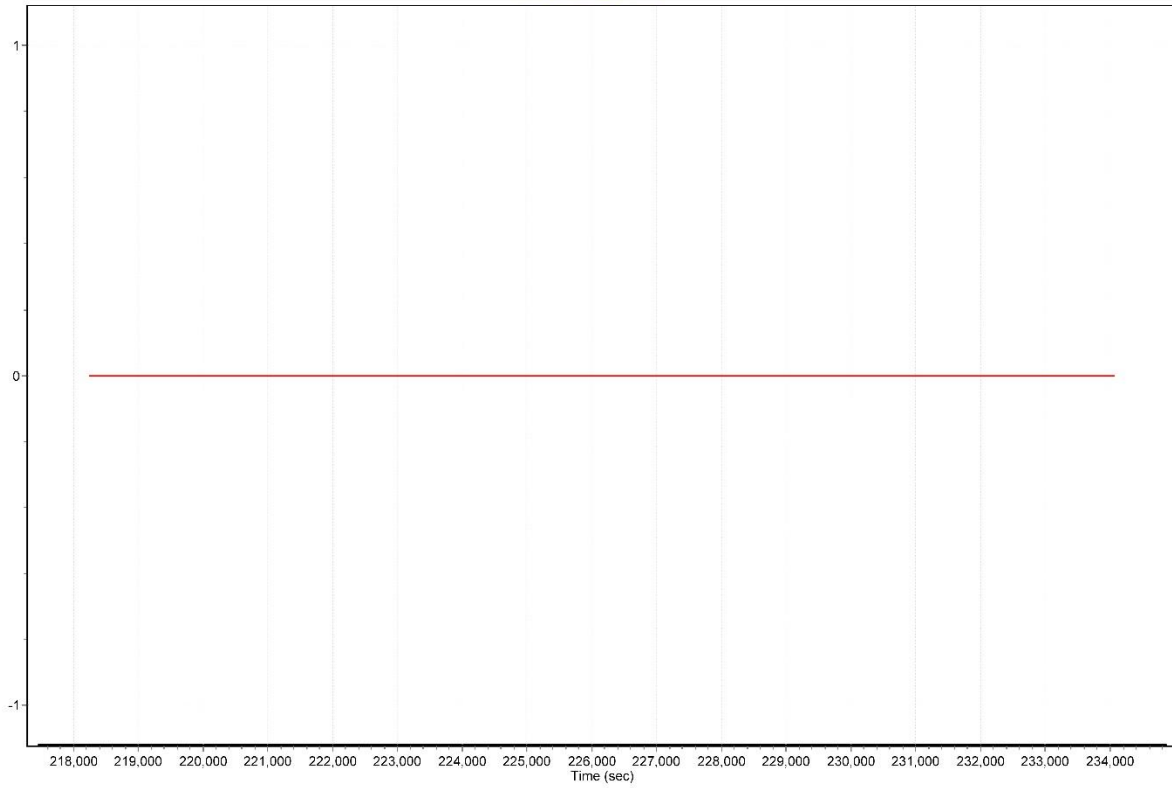








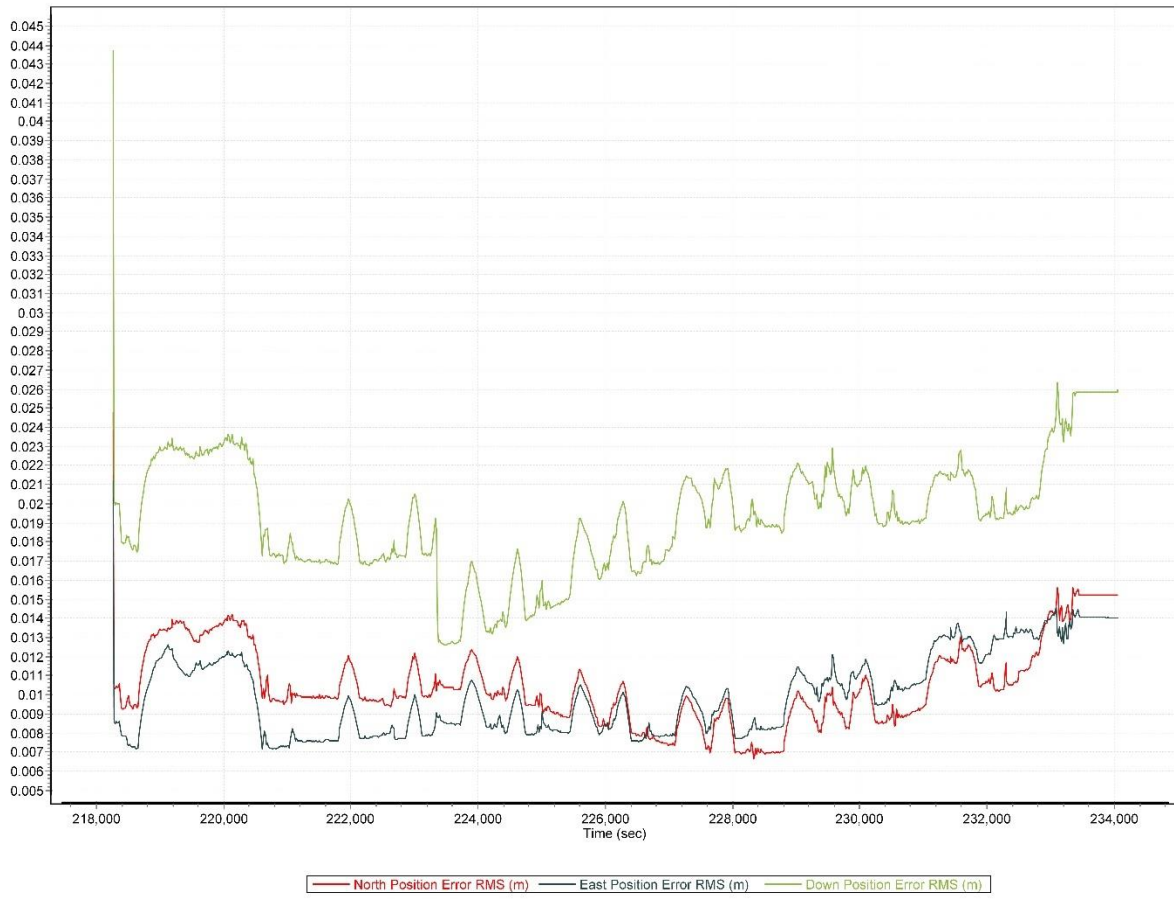
Processing mode

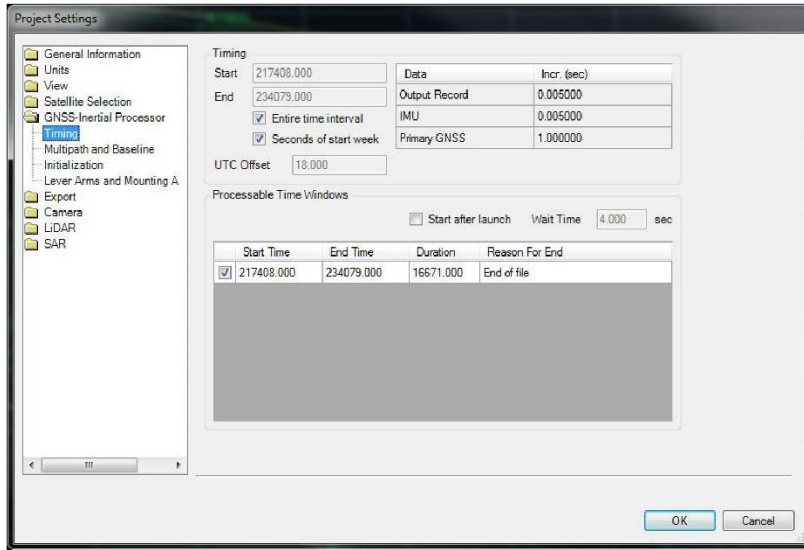


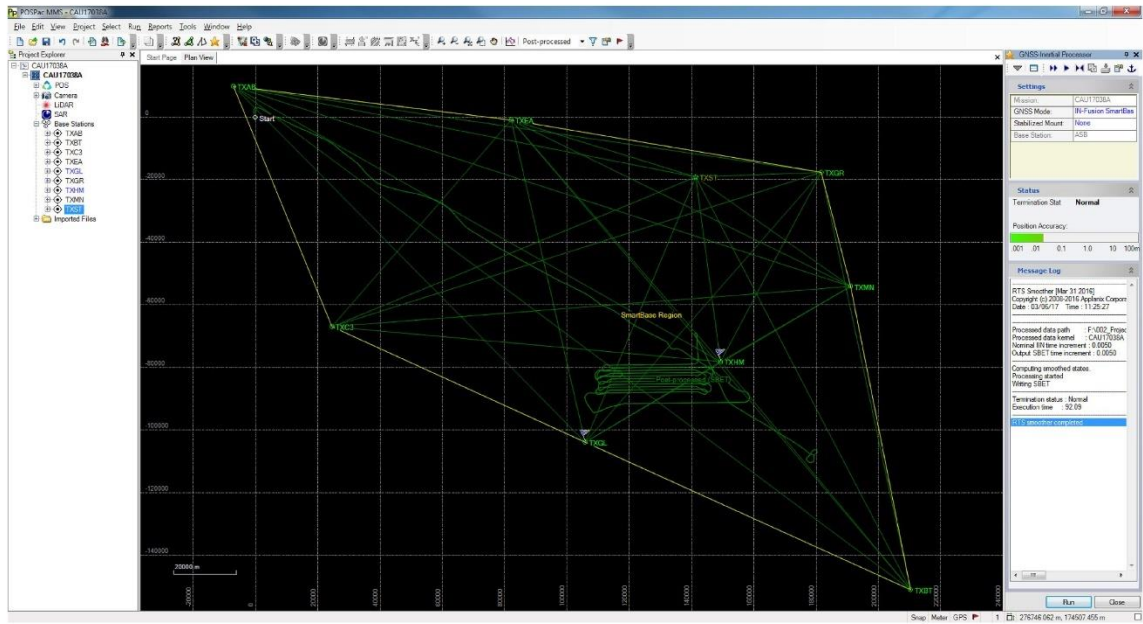
Forward Reverse

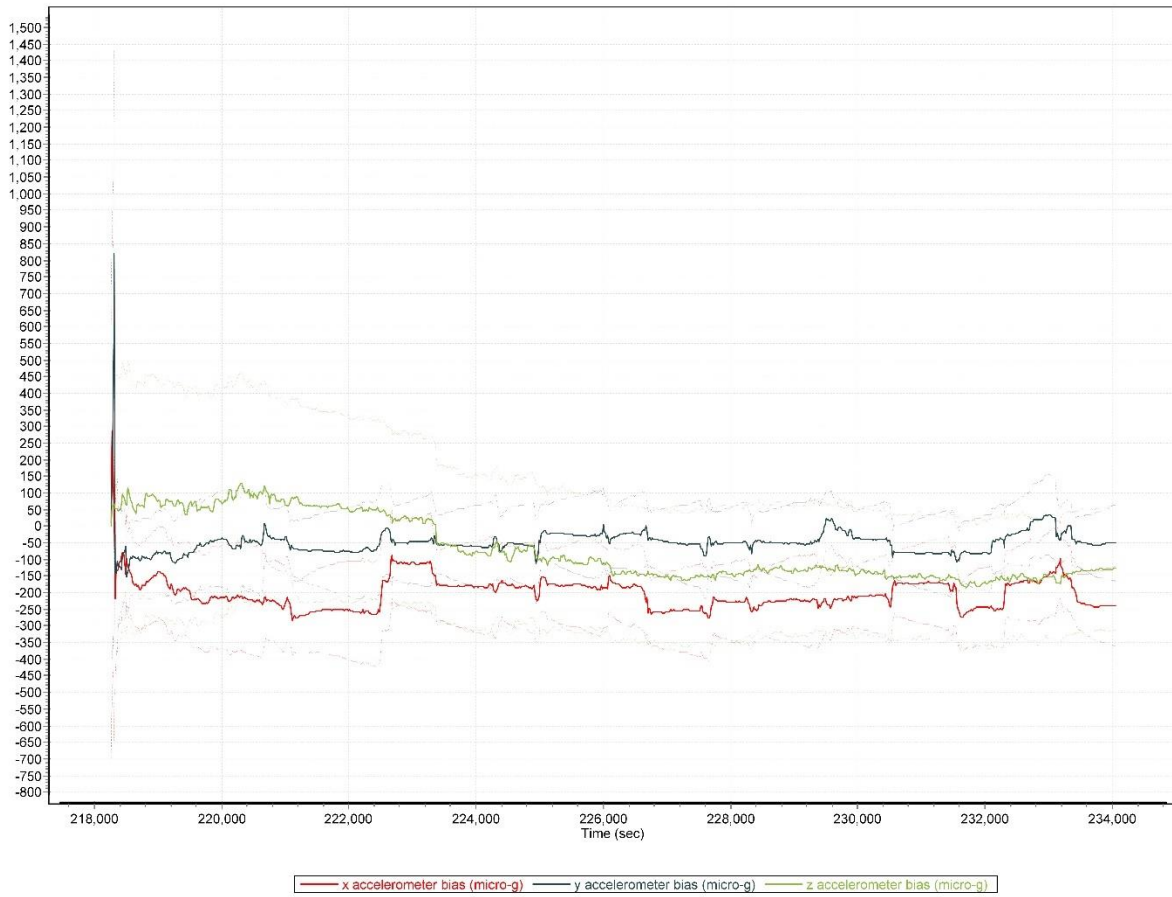
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IAPPP, 6 = C/A, 7 = GNSS Nav, 8 = DR



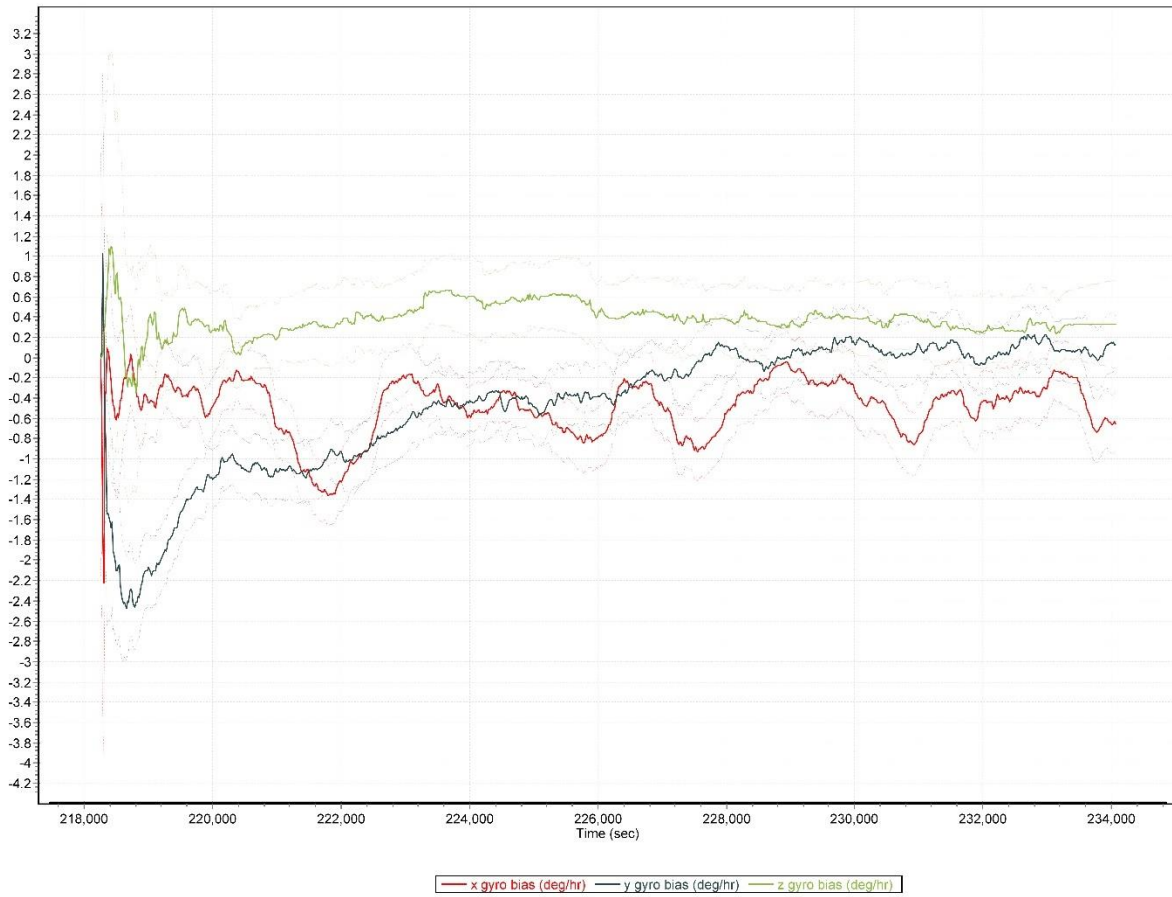






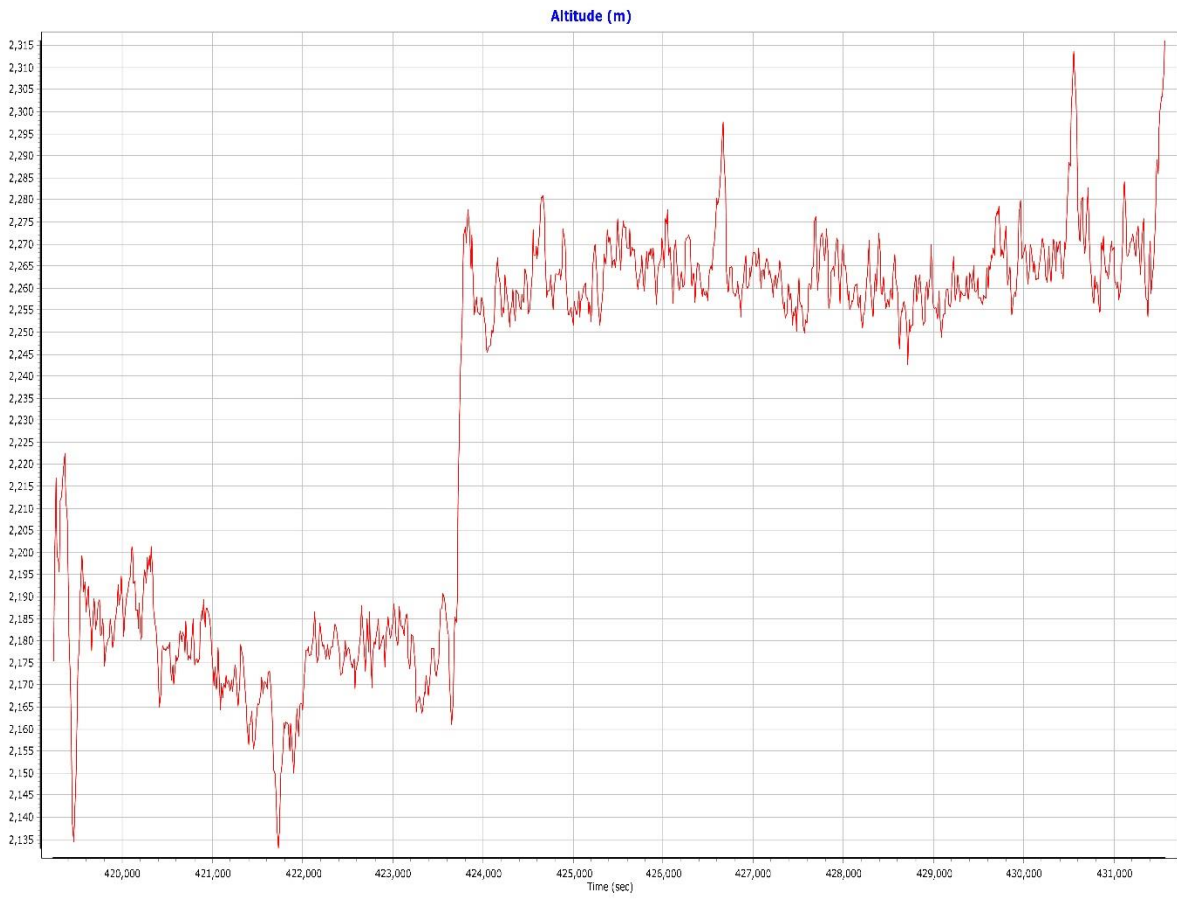


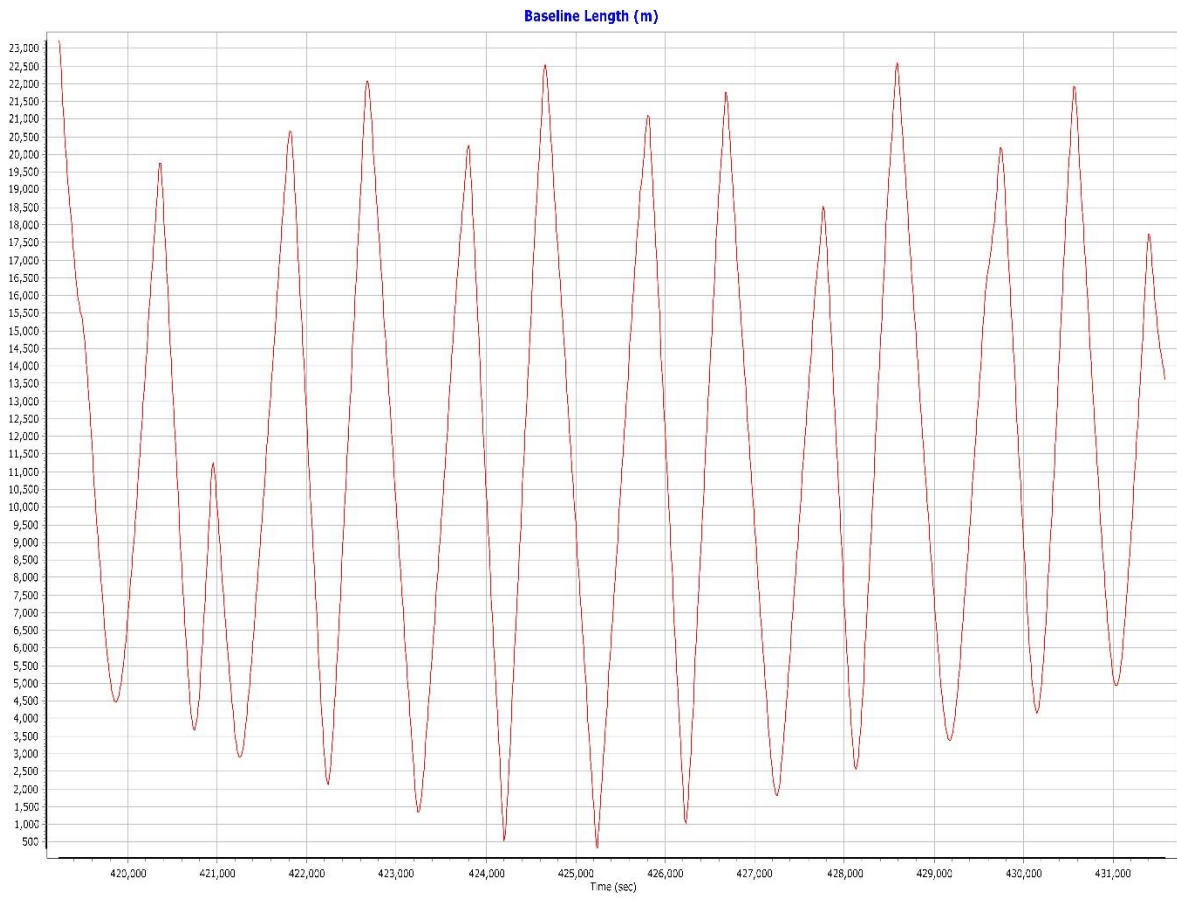


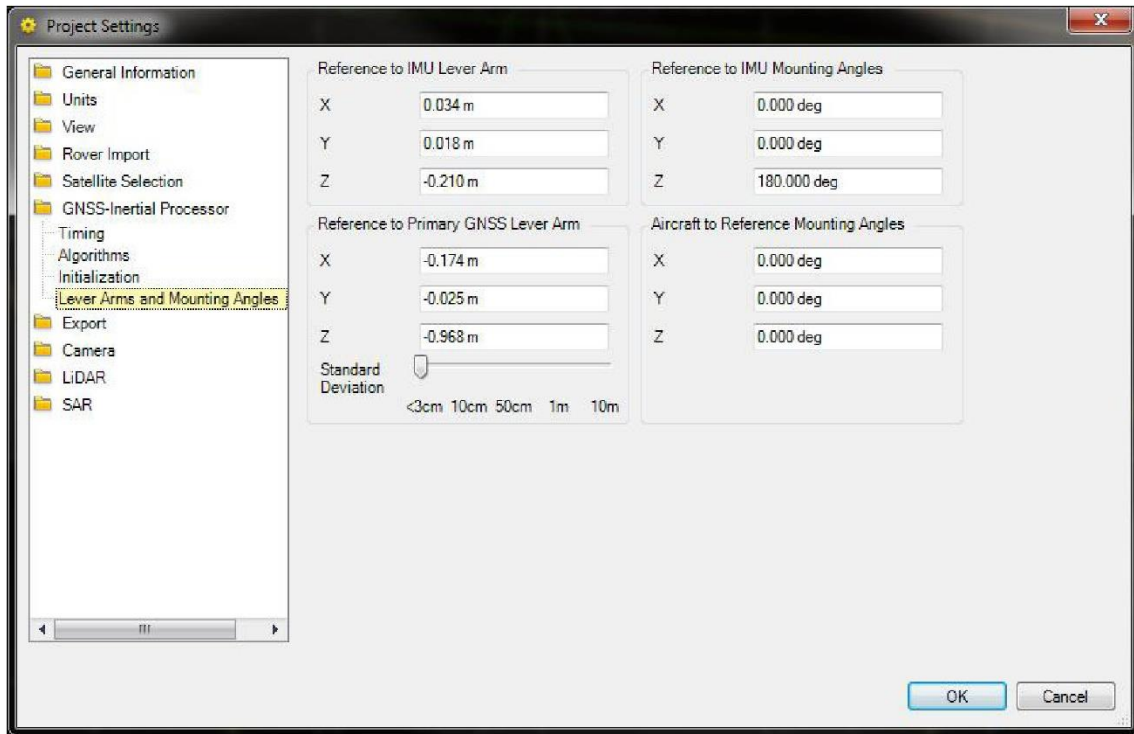


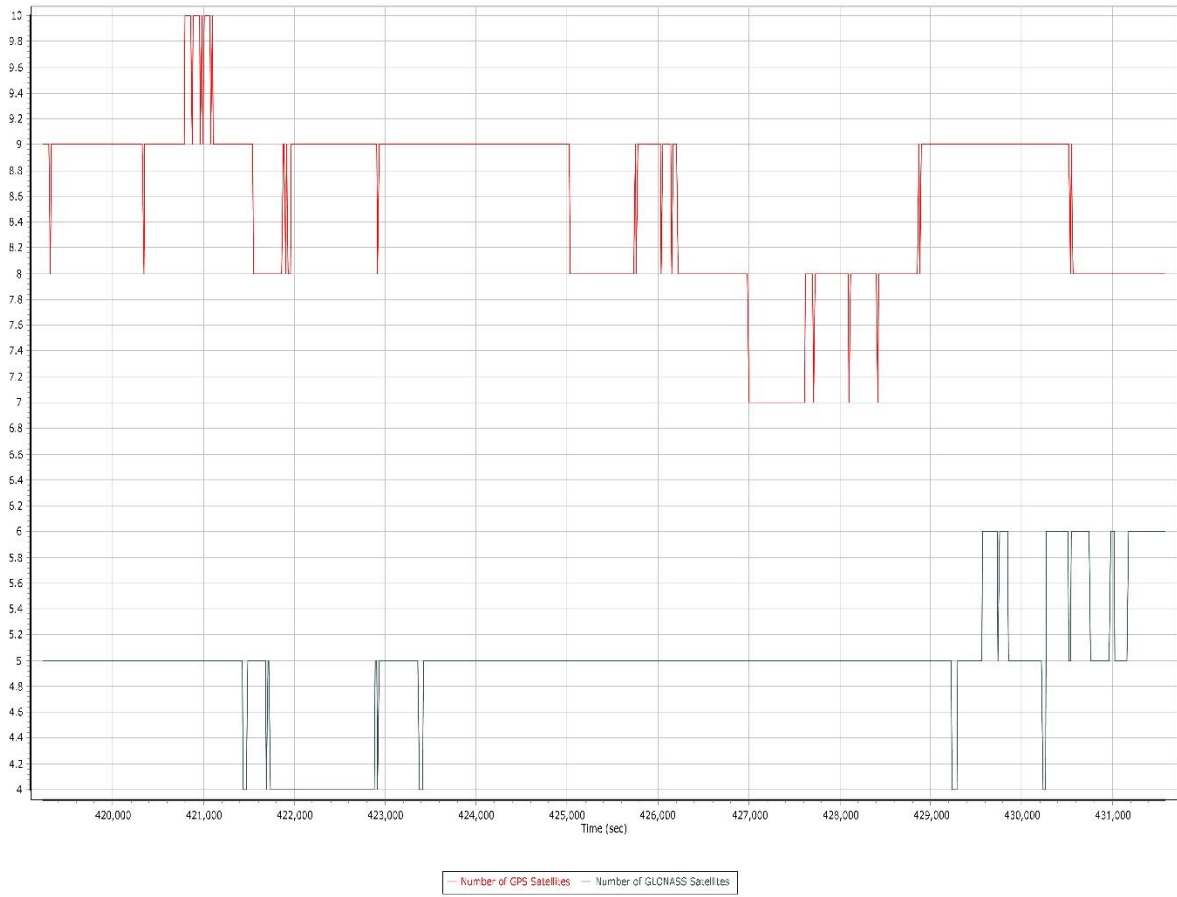


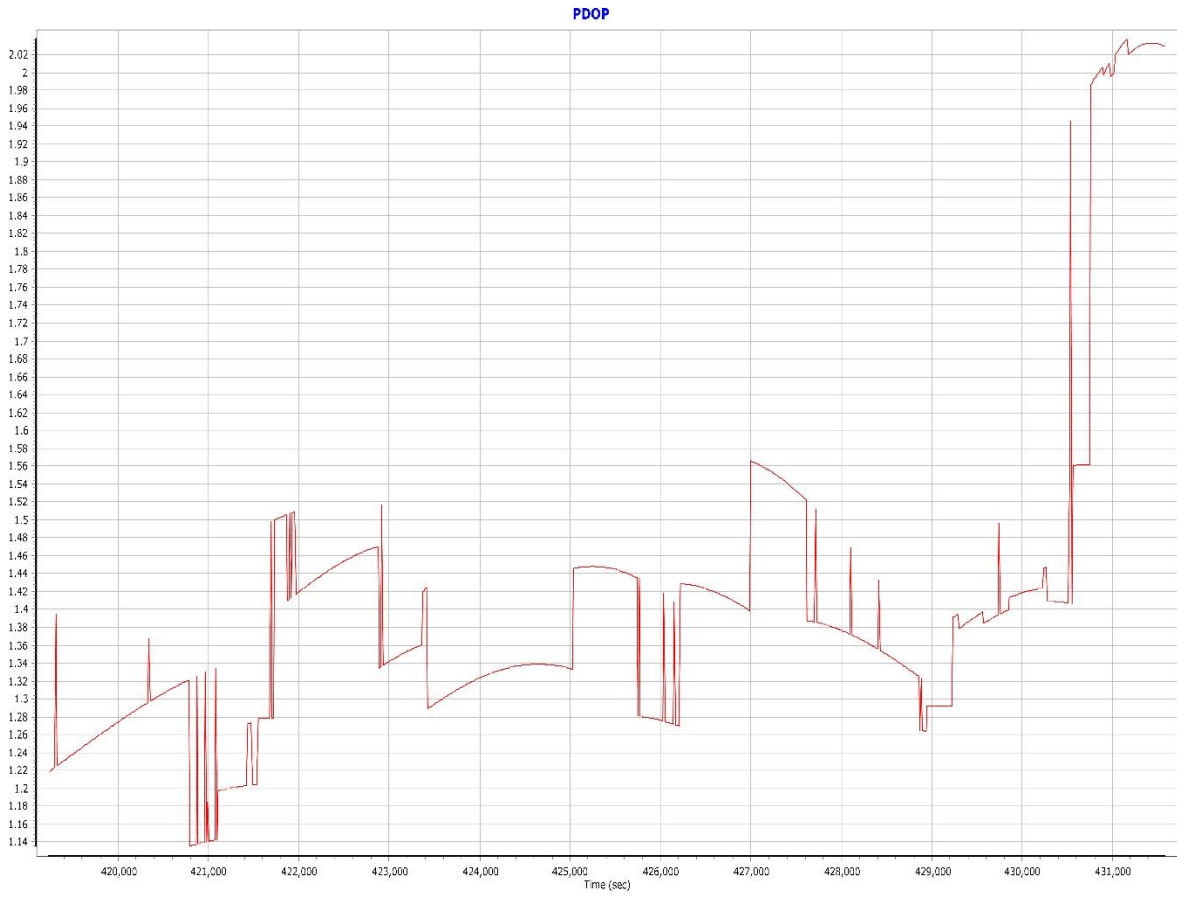
CAU18032B

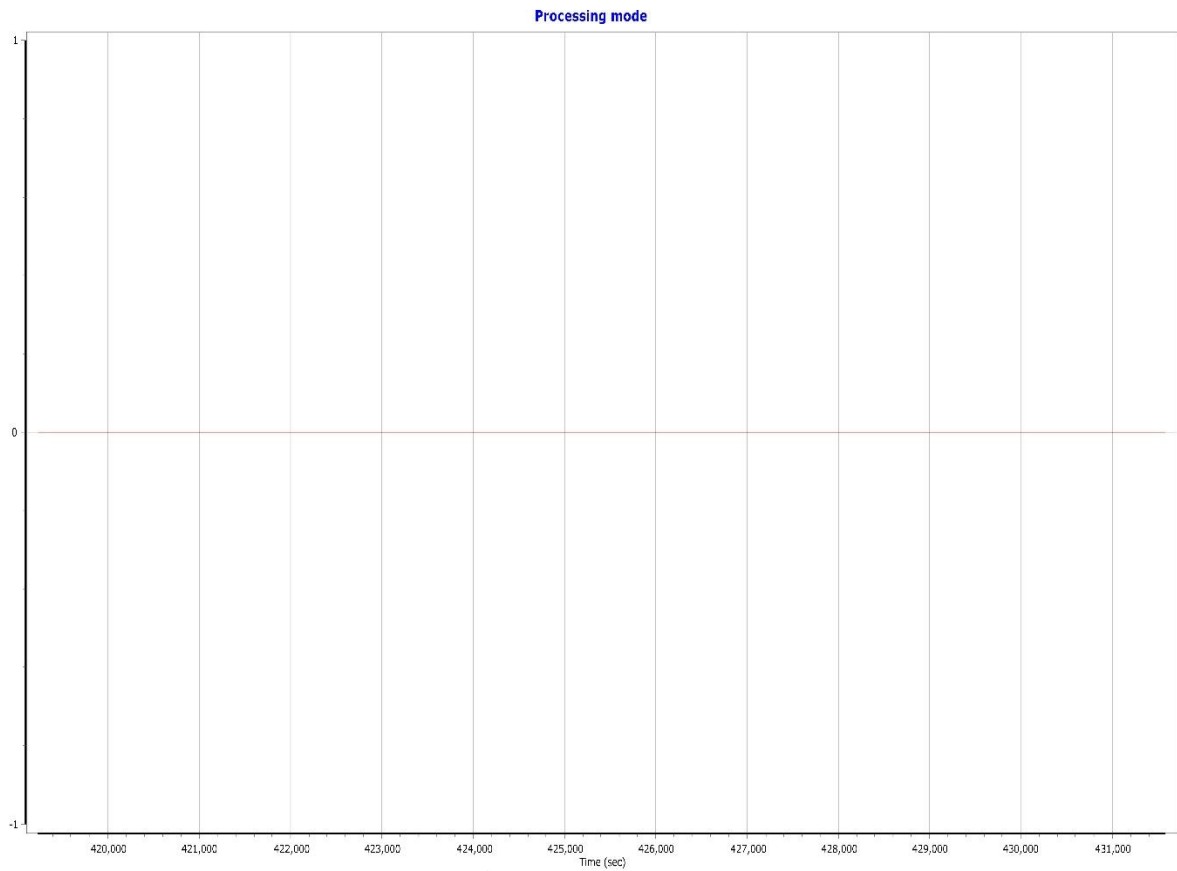




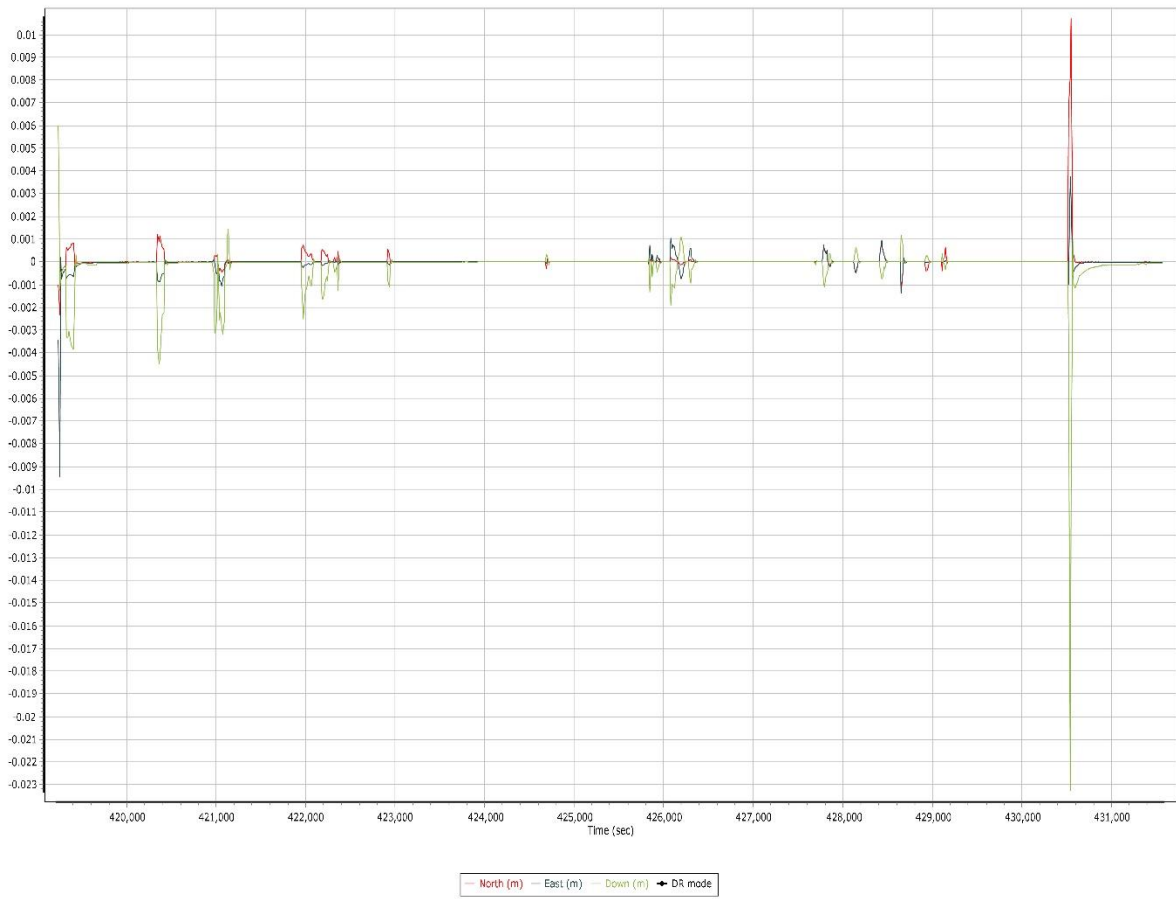




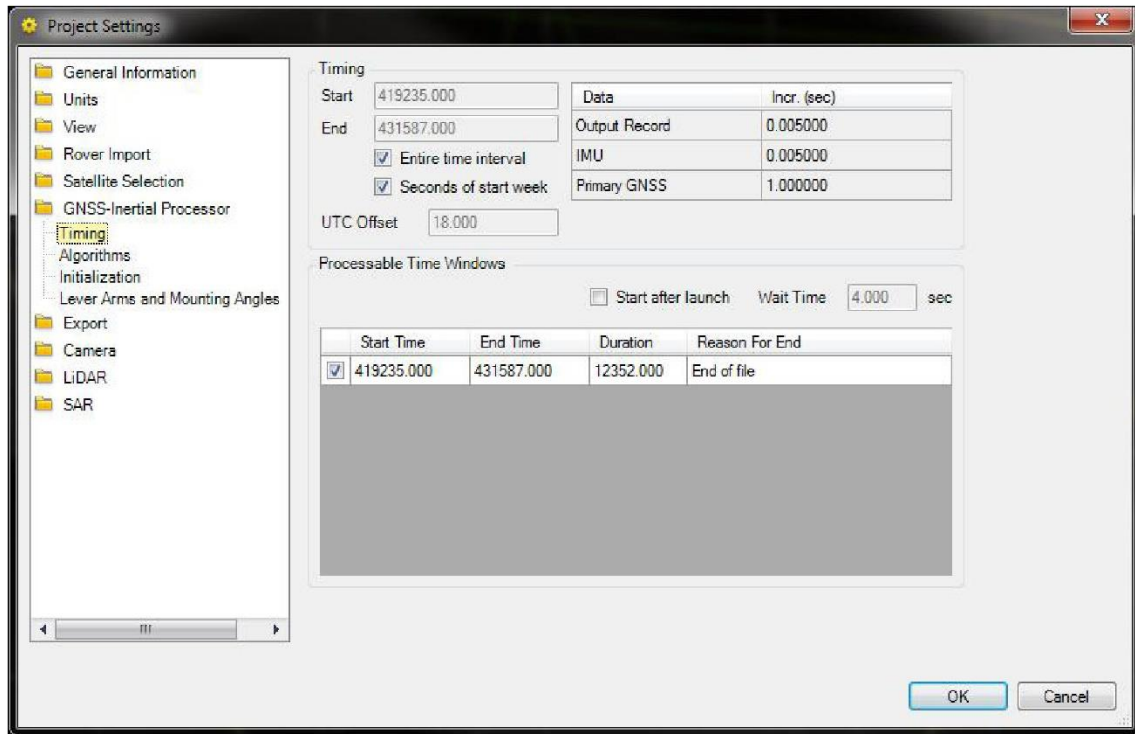


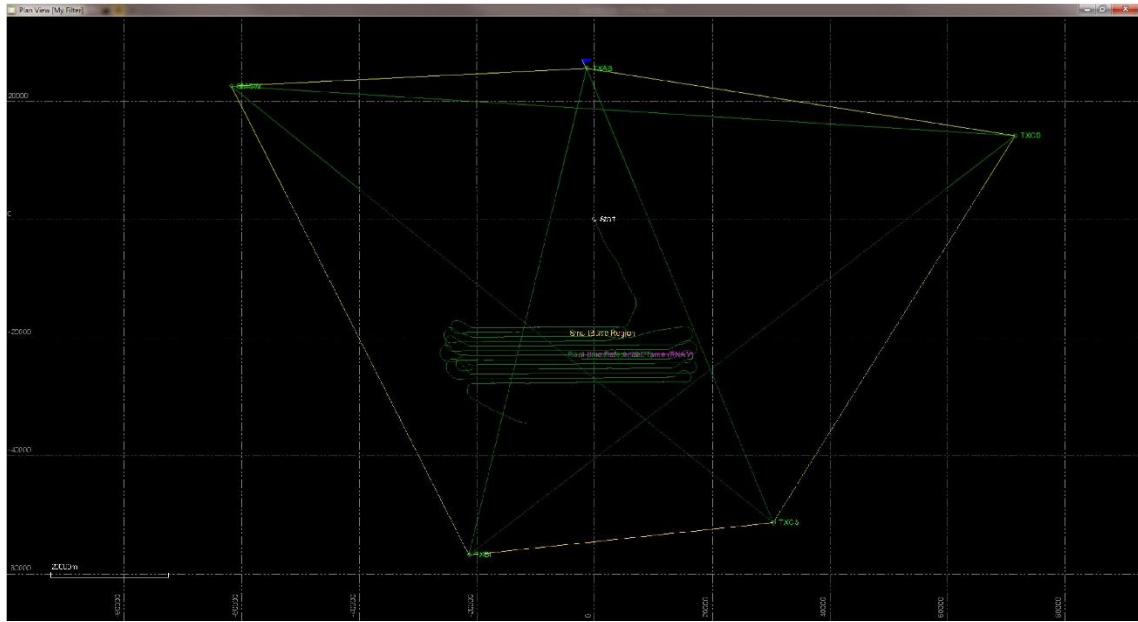


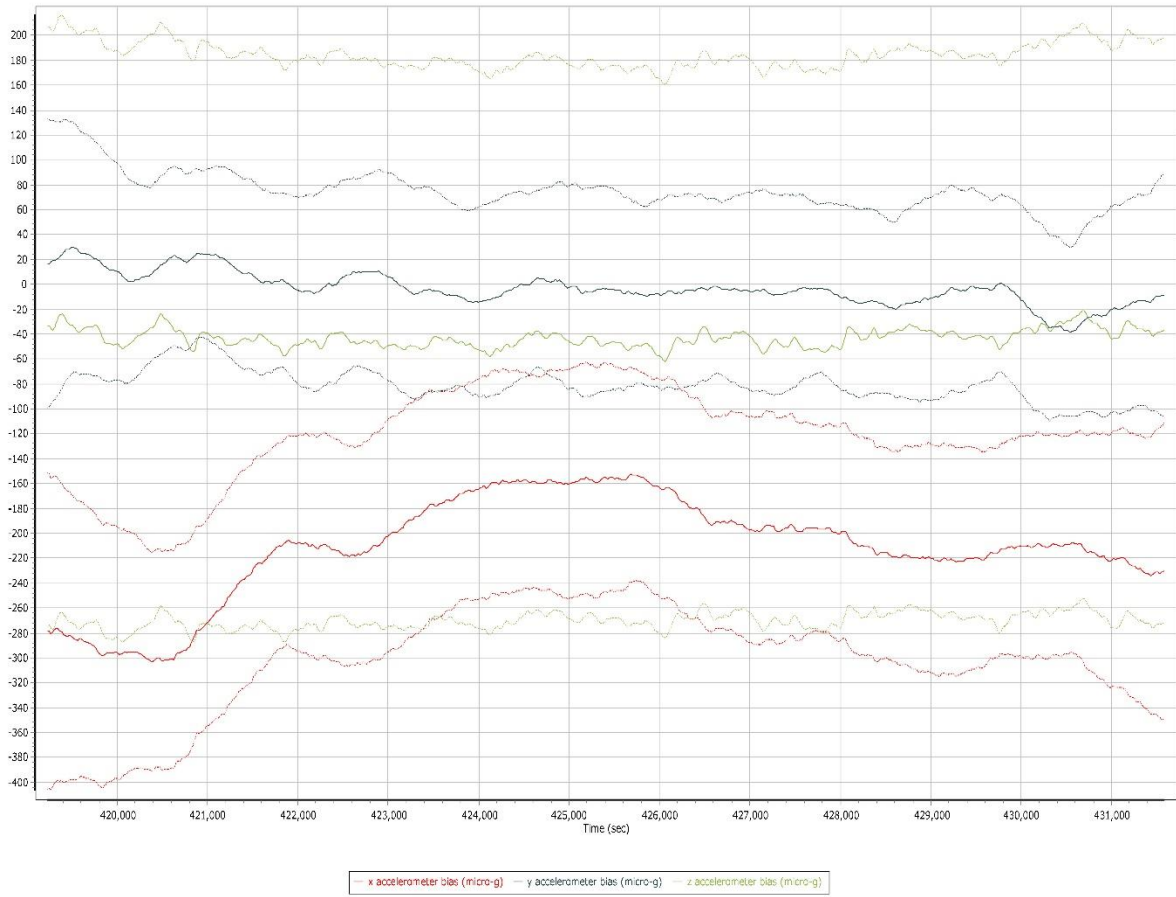
0 = Fixed NL, 1 = fixed WL, 2 = float, 3 = DGNSS, 4 = RTCM, 5 = IA PPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

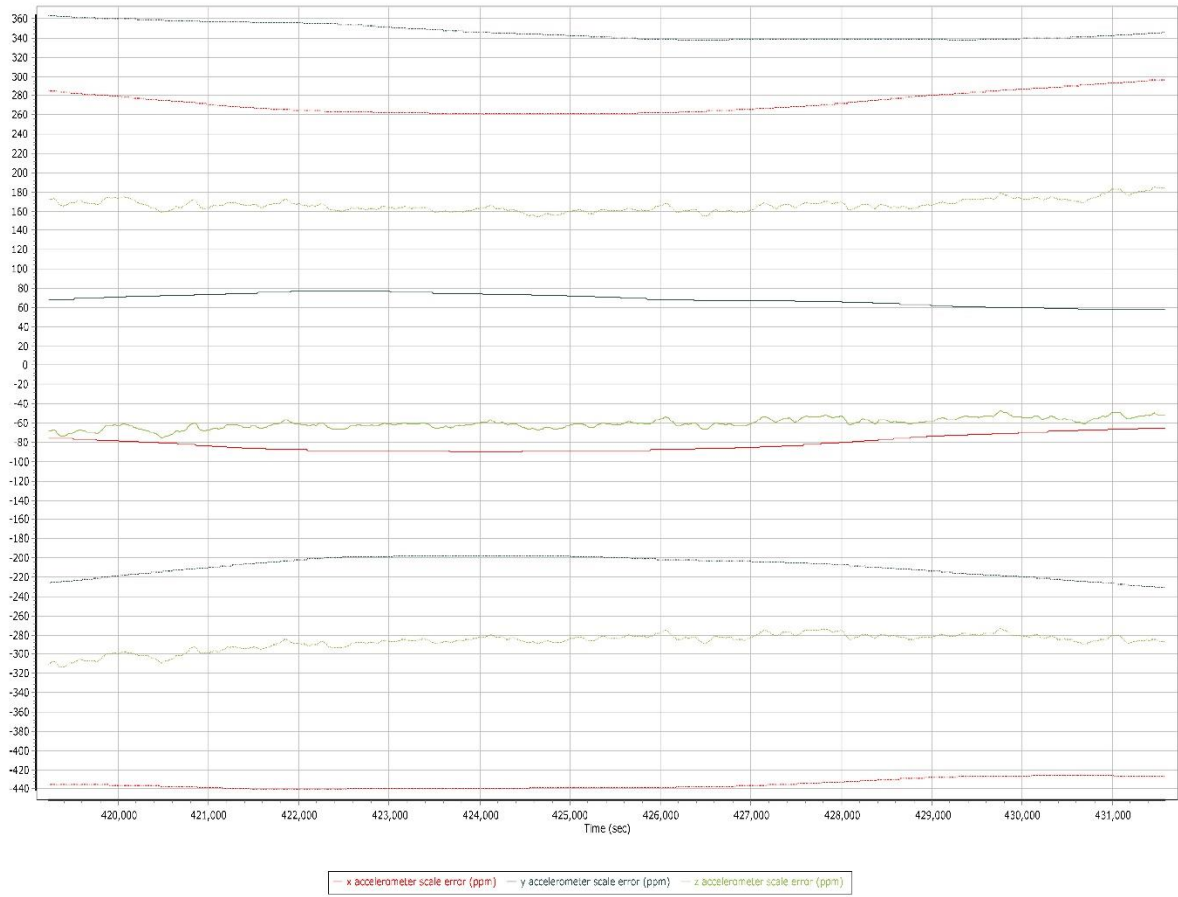


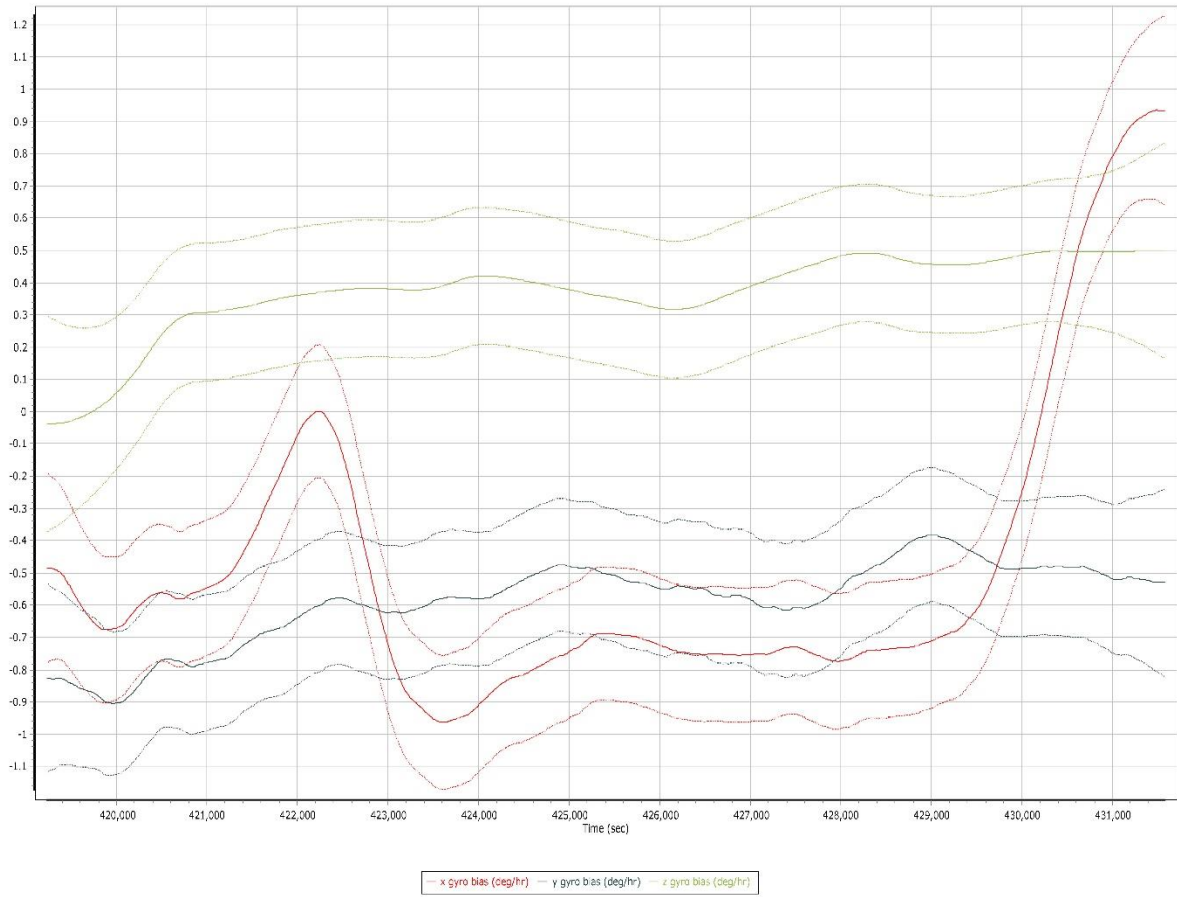


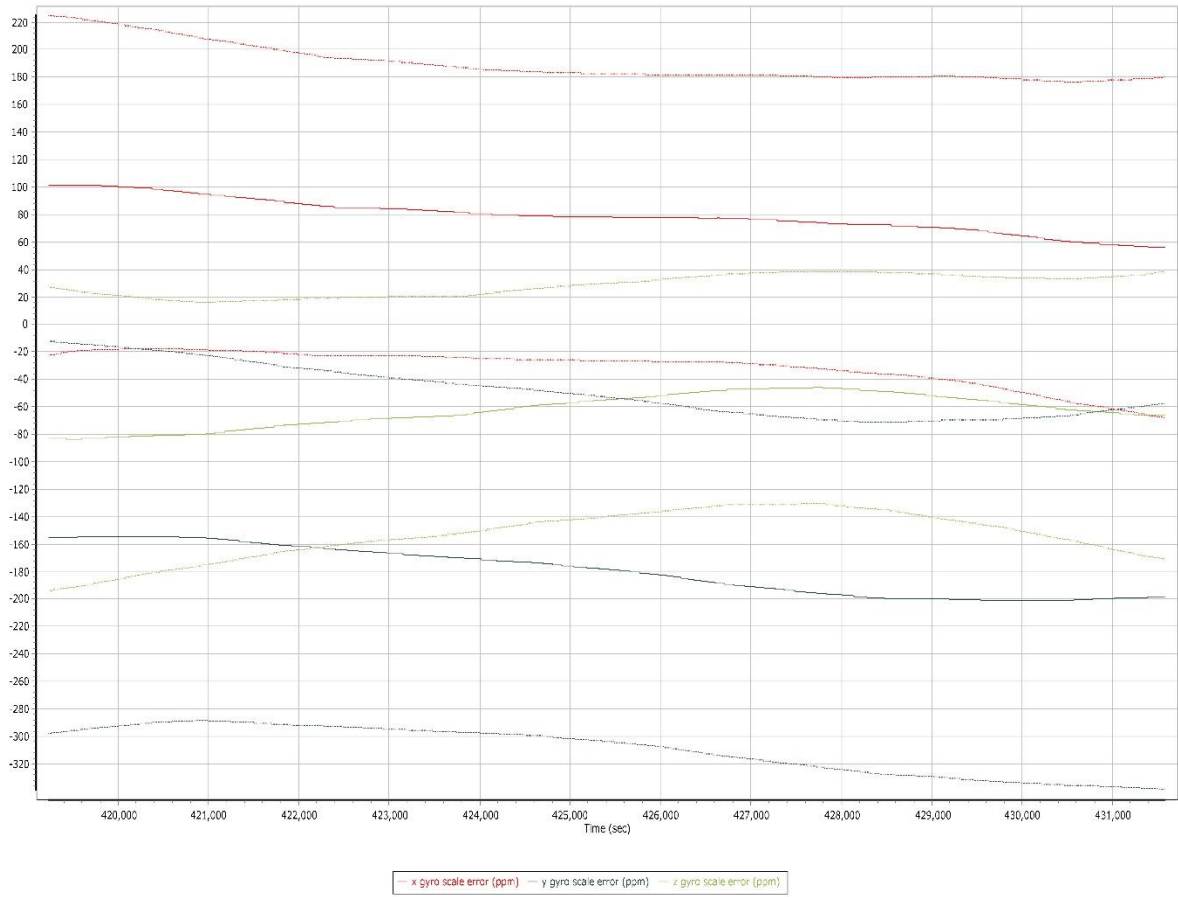




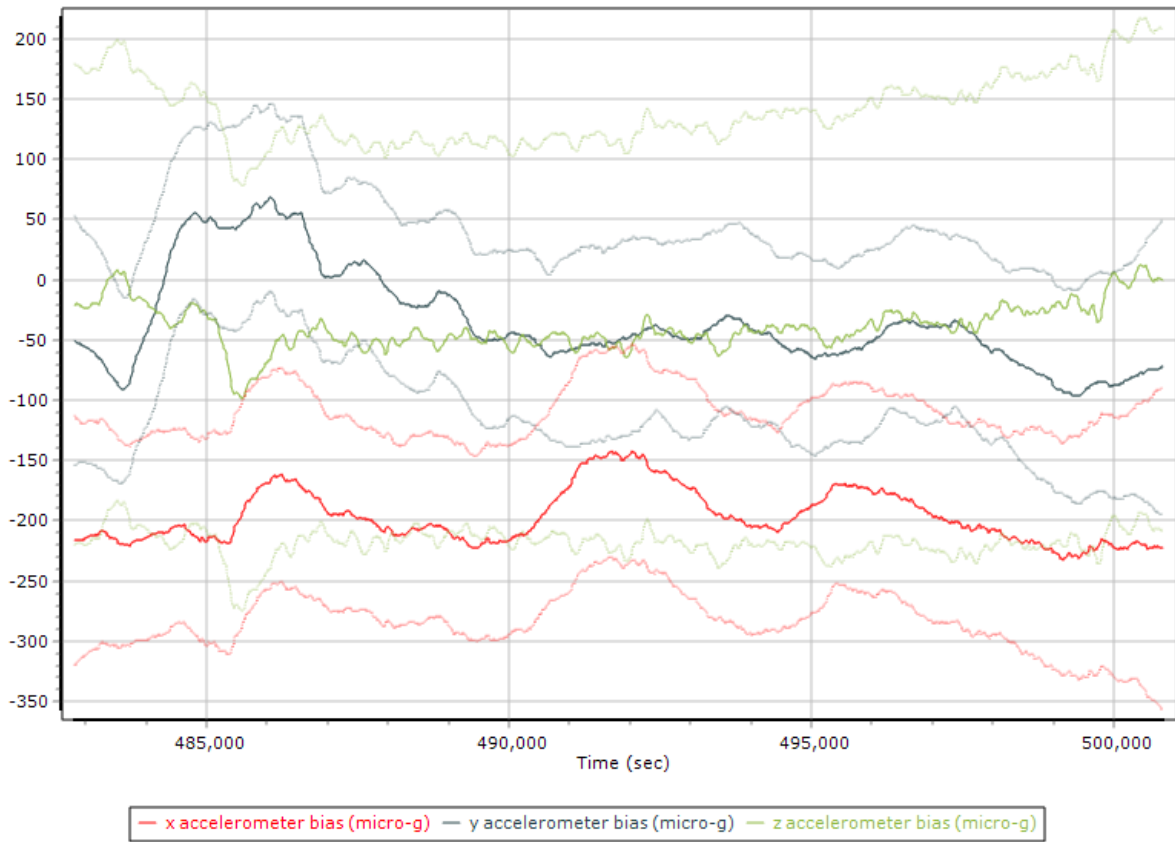


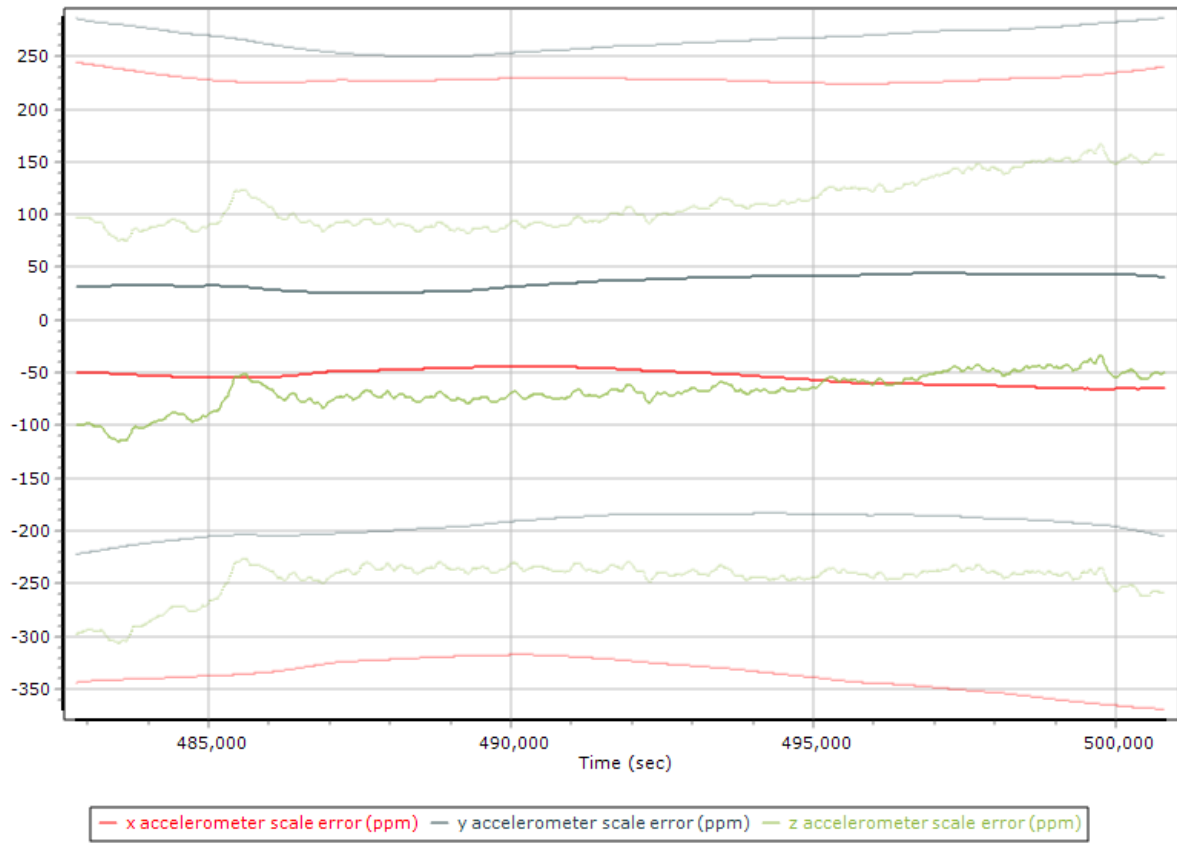


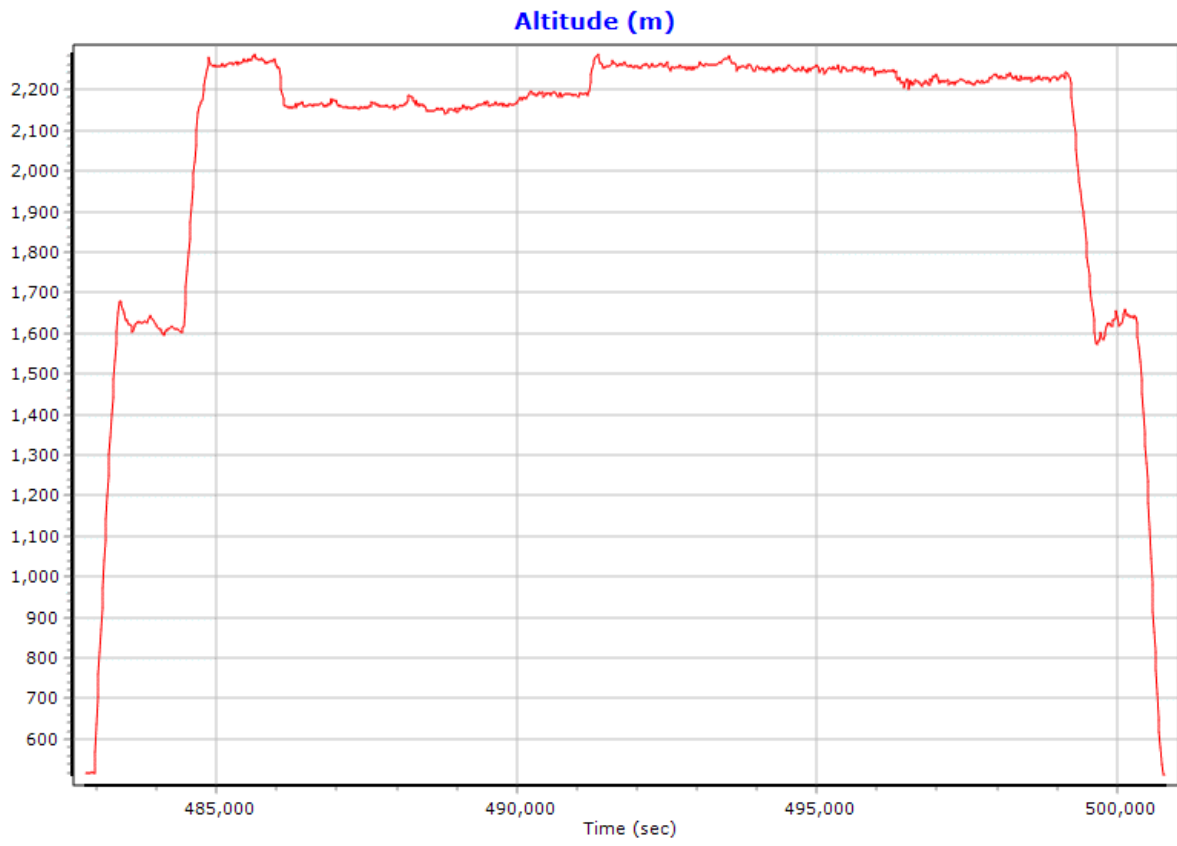


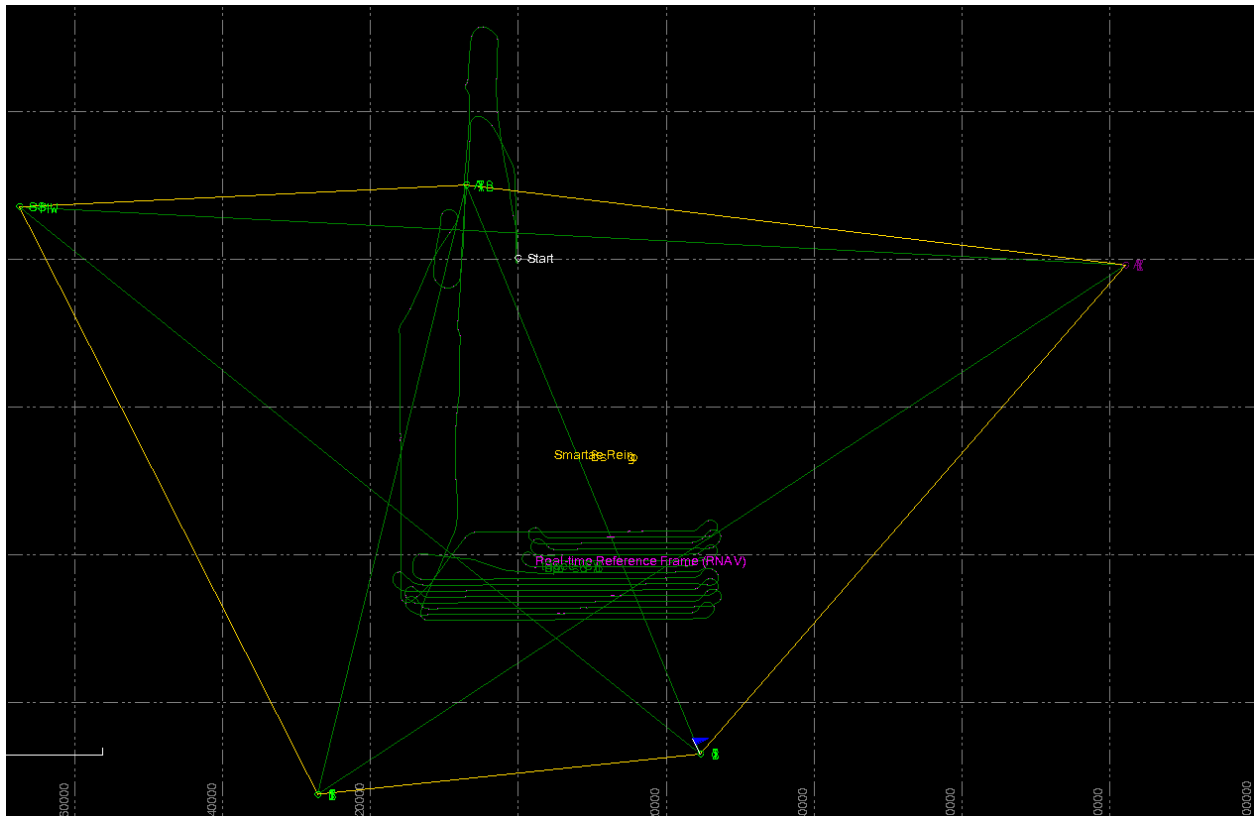
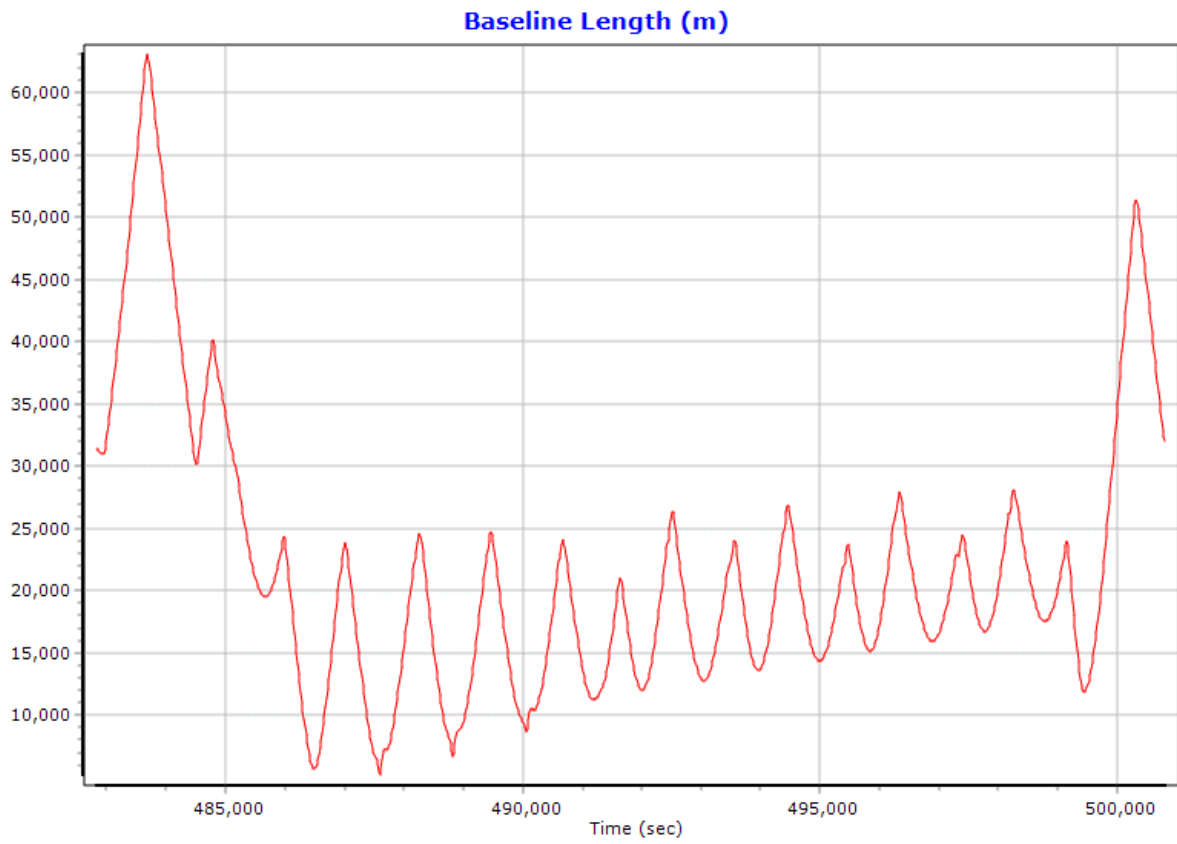


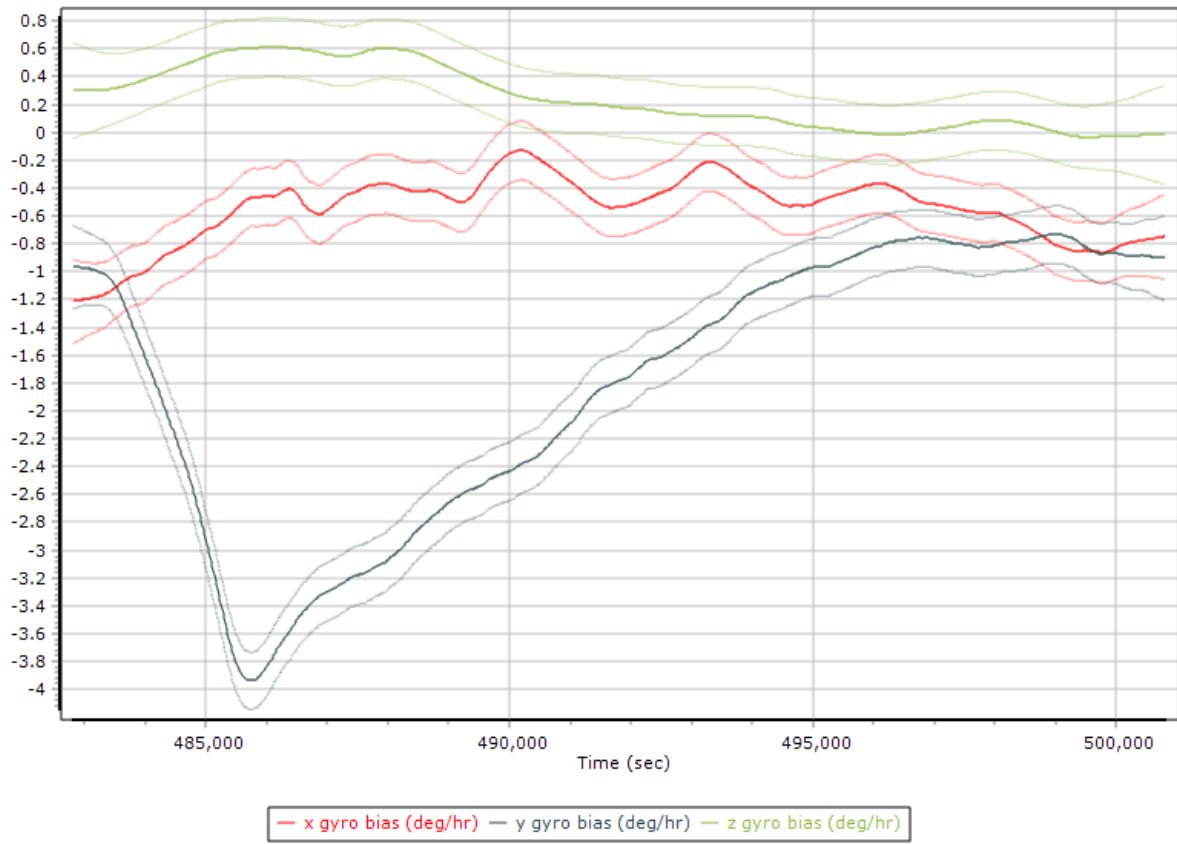
CAU18033A

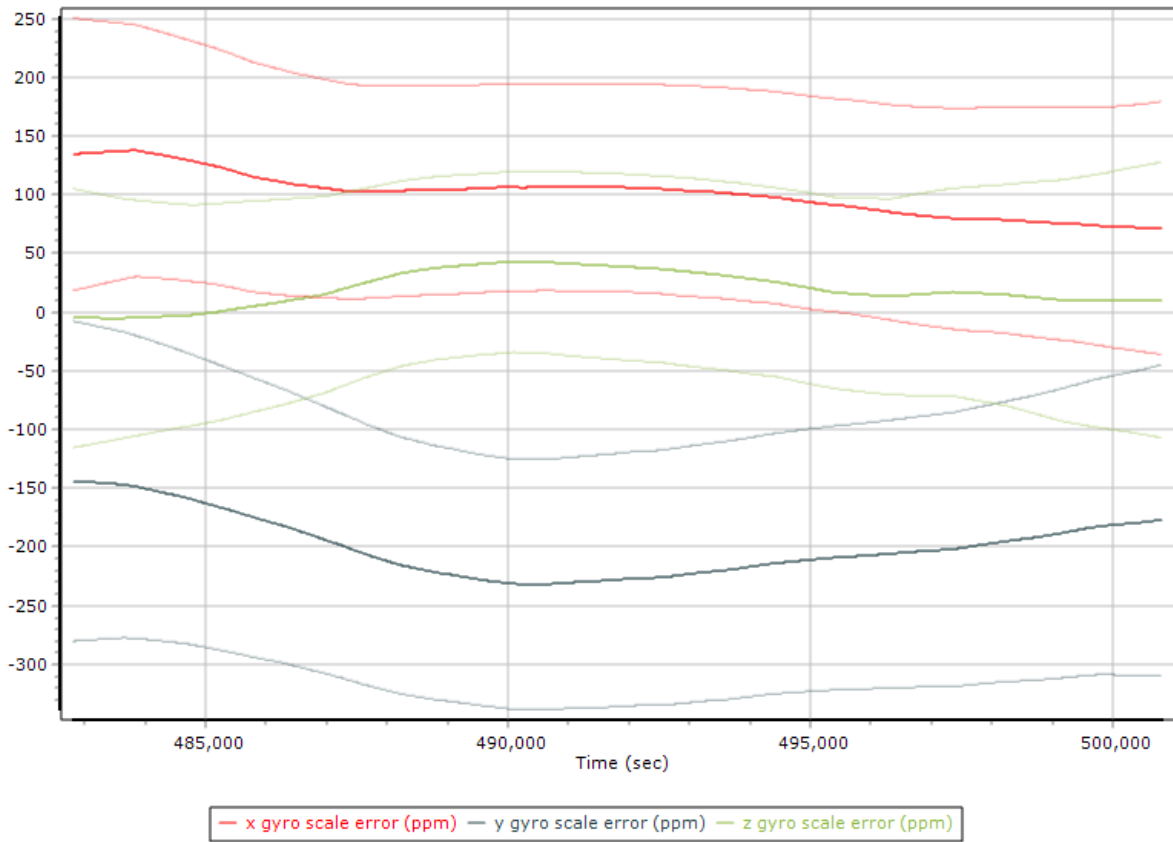












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

Aircraft to Reference Mounting Angles

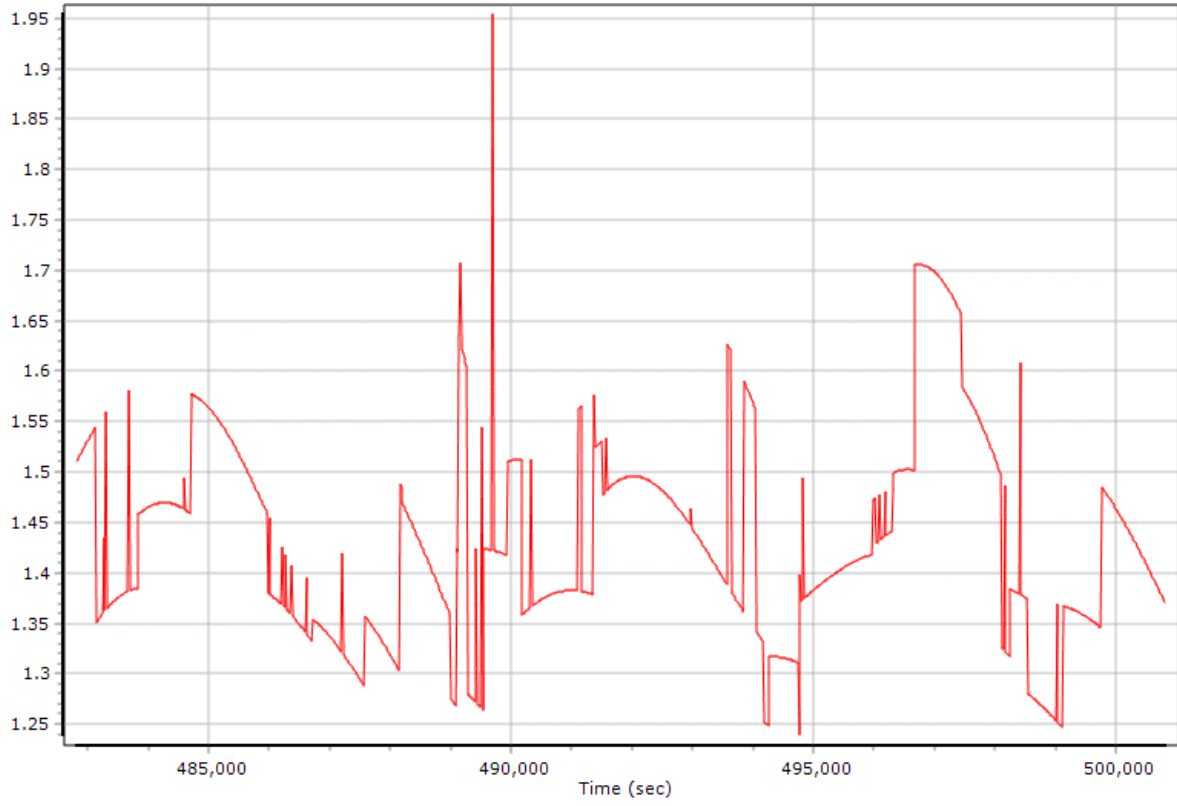
X:

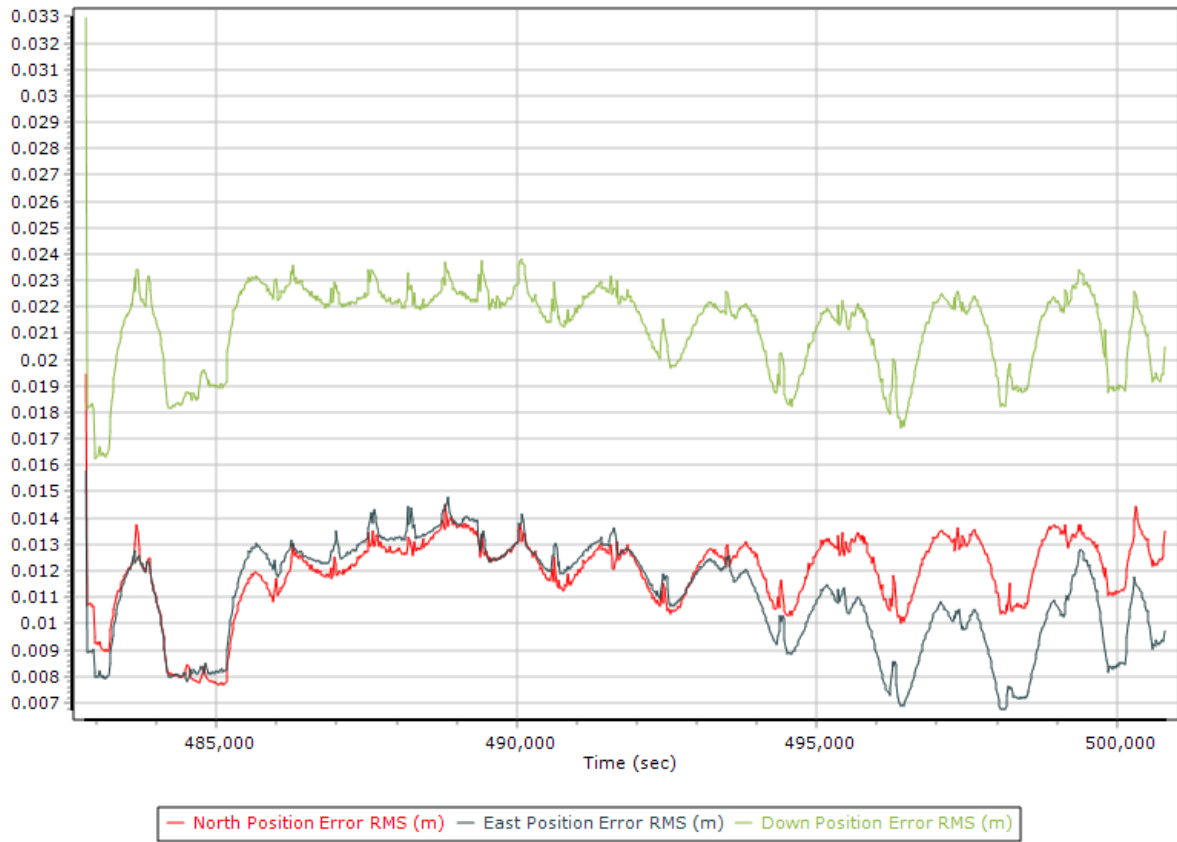
Y:

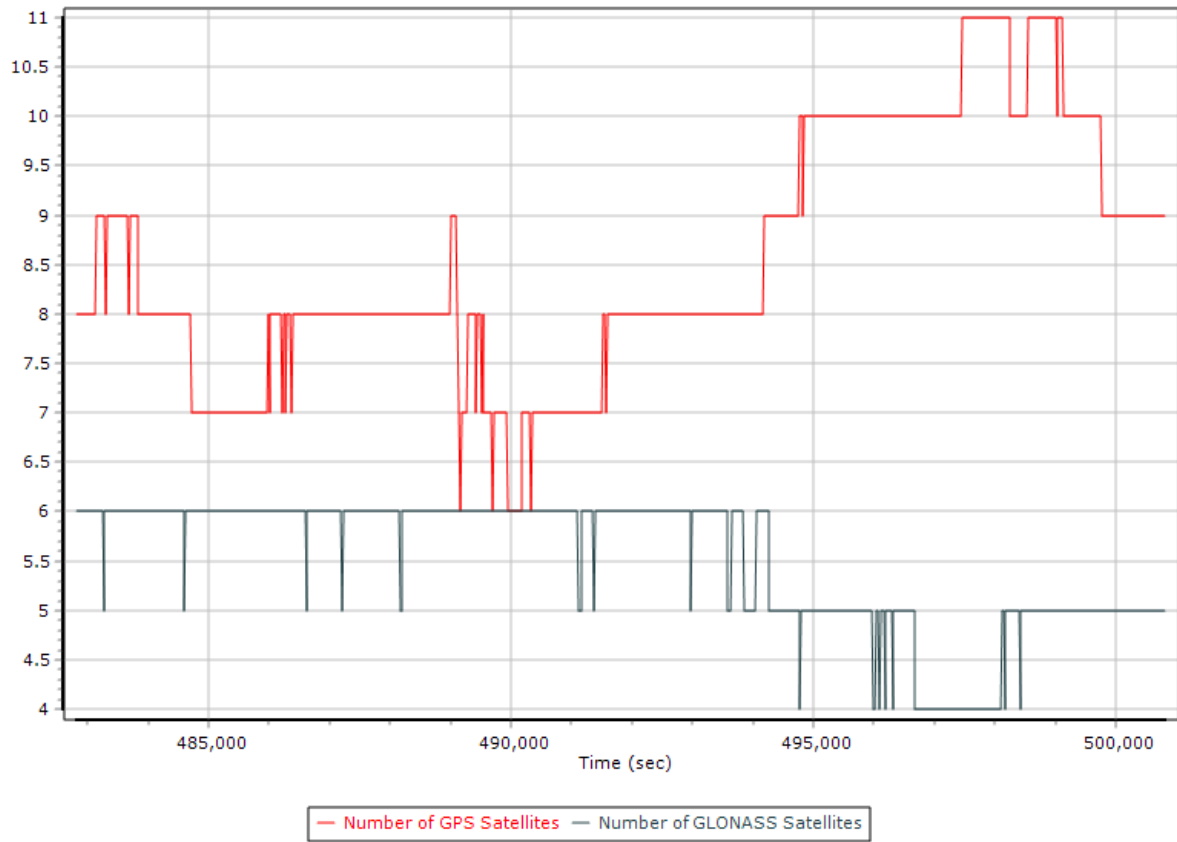
Z:

OK Cancel

PDOP









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: 482243.000
 End: 500834.000
 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

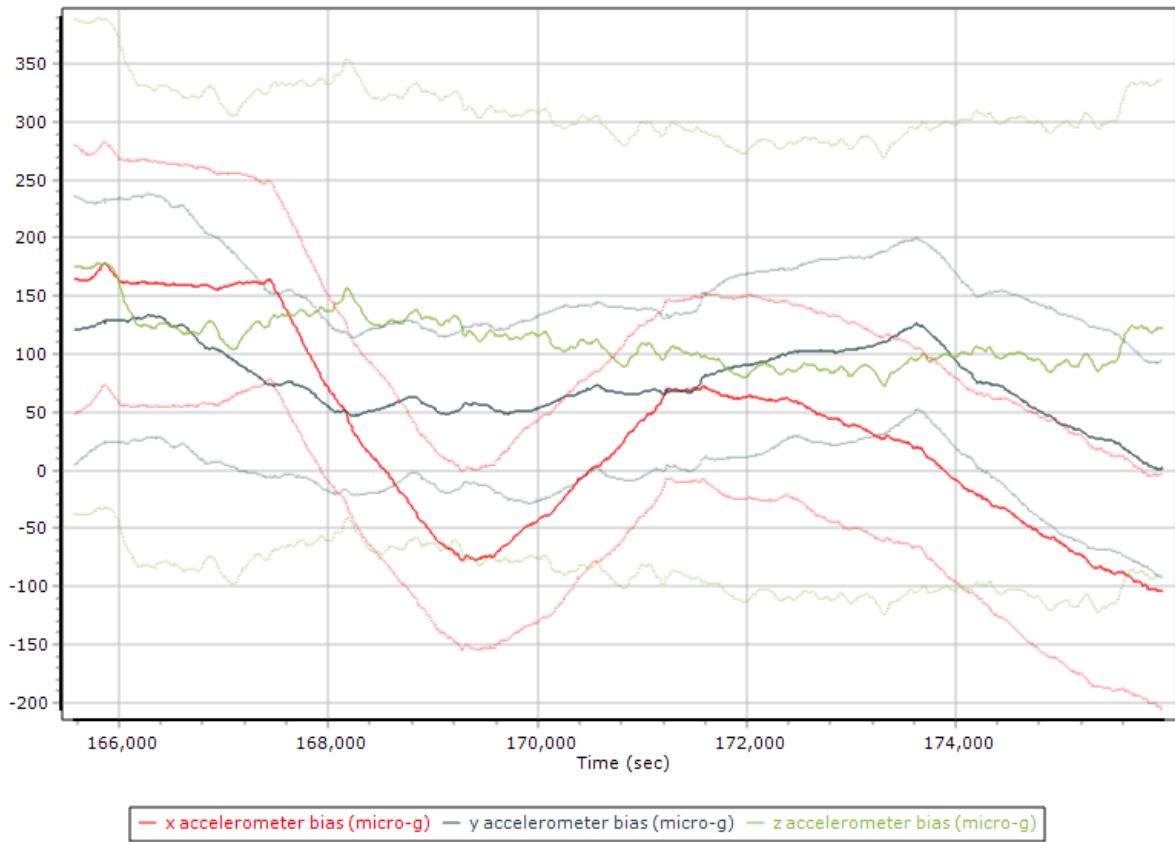
Processable Time Windows

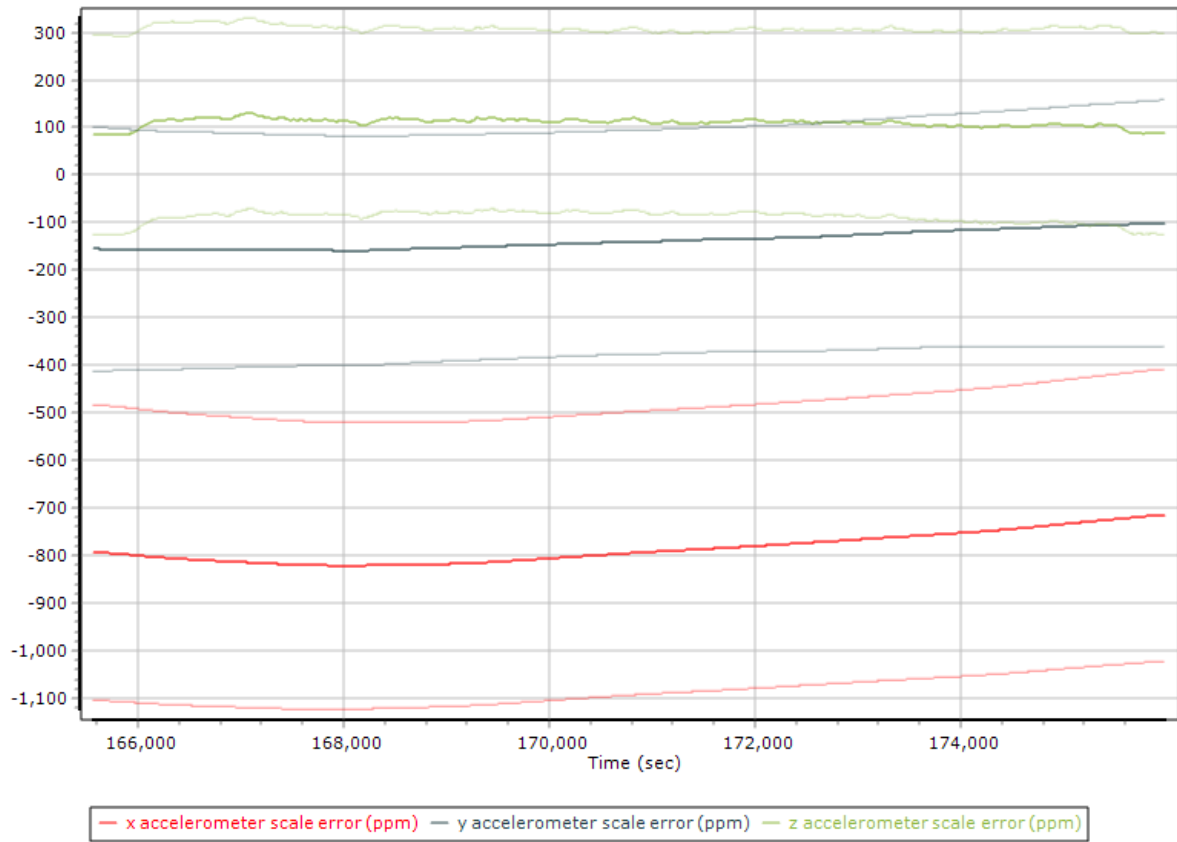
Start after launch Wait Time: 4.000 sec

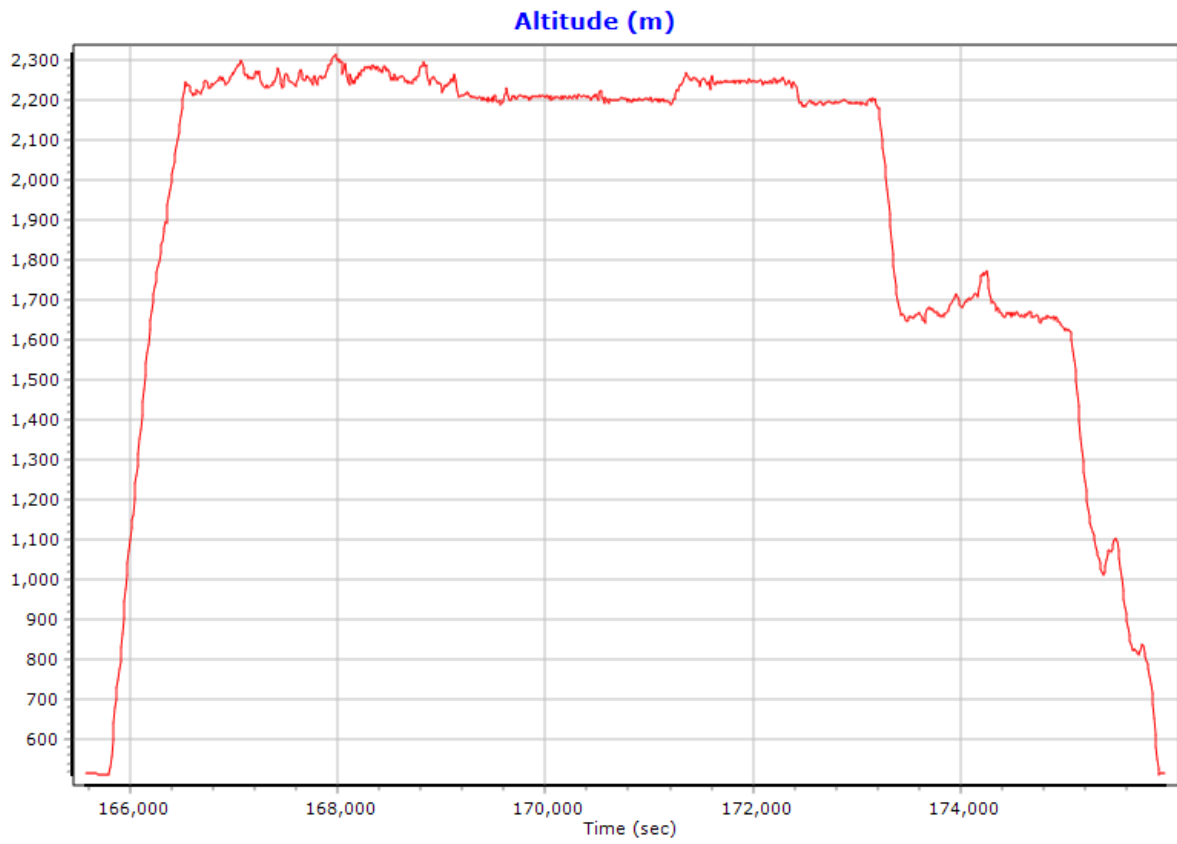
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	482243.000	500834.000	18591.000	End of file

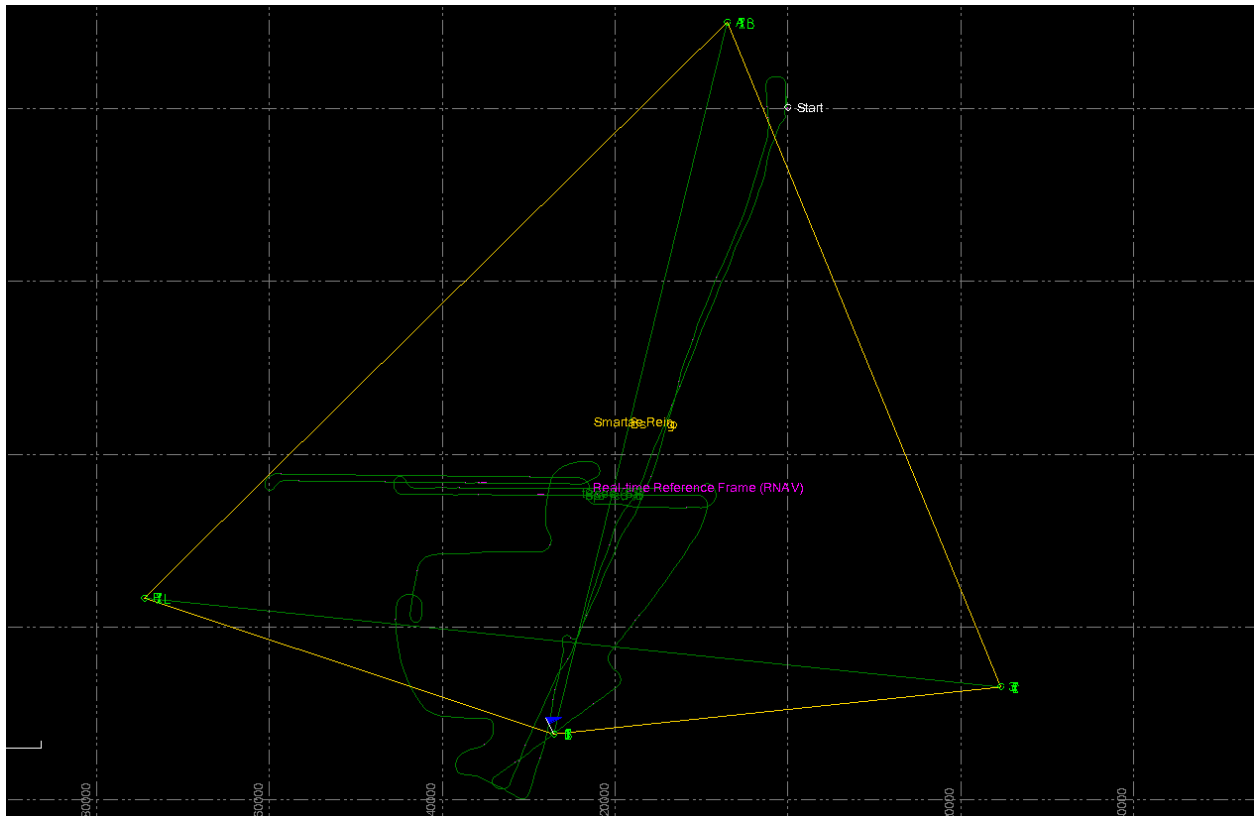
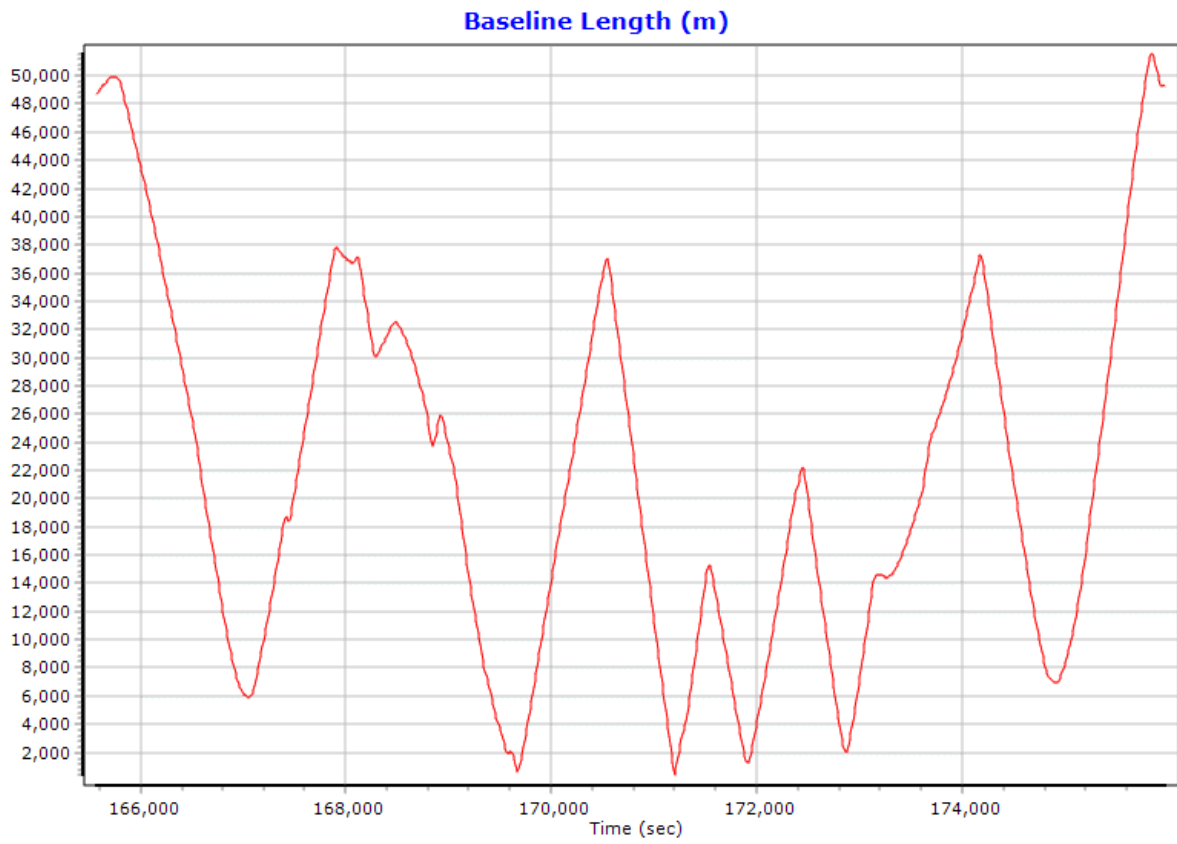
OK Cancel

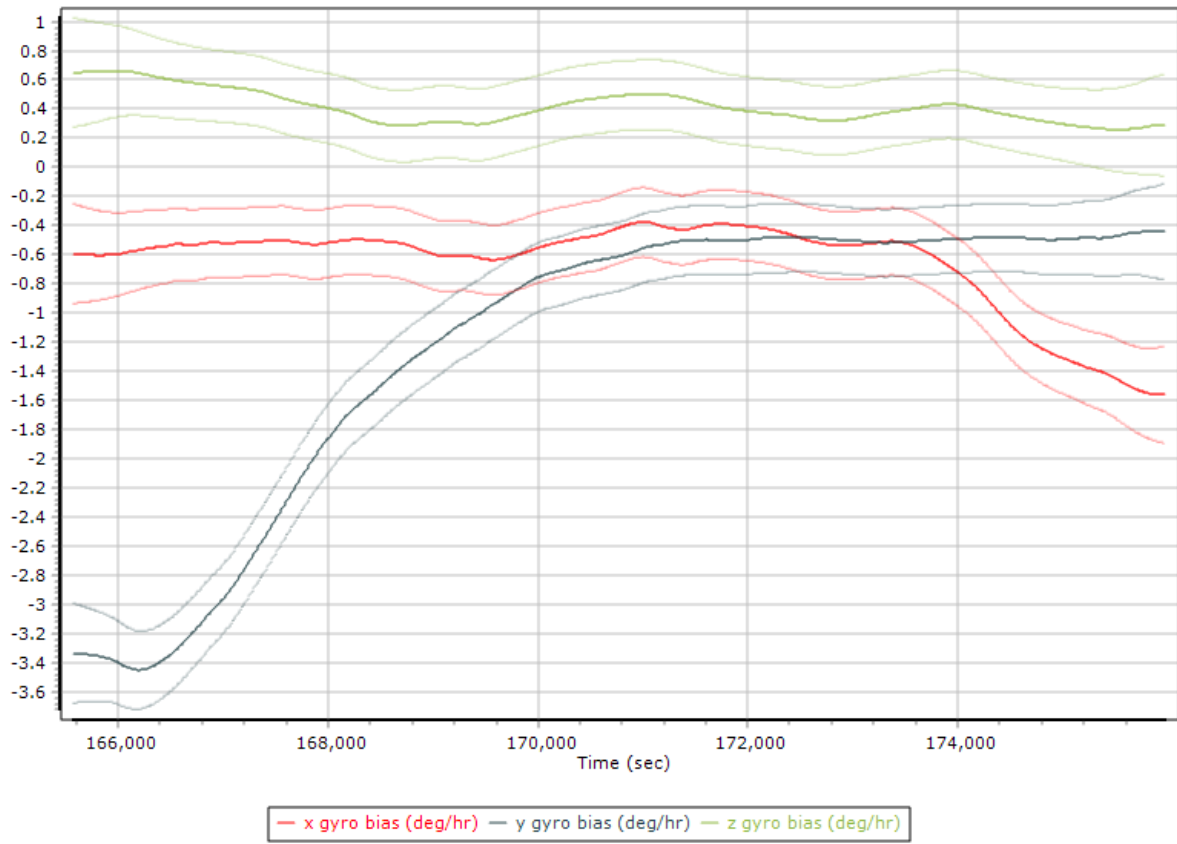
CAU18036A

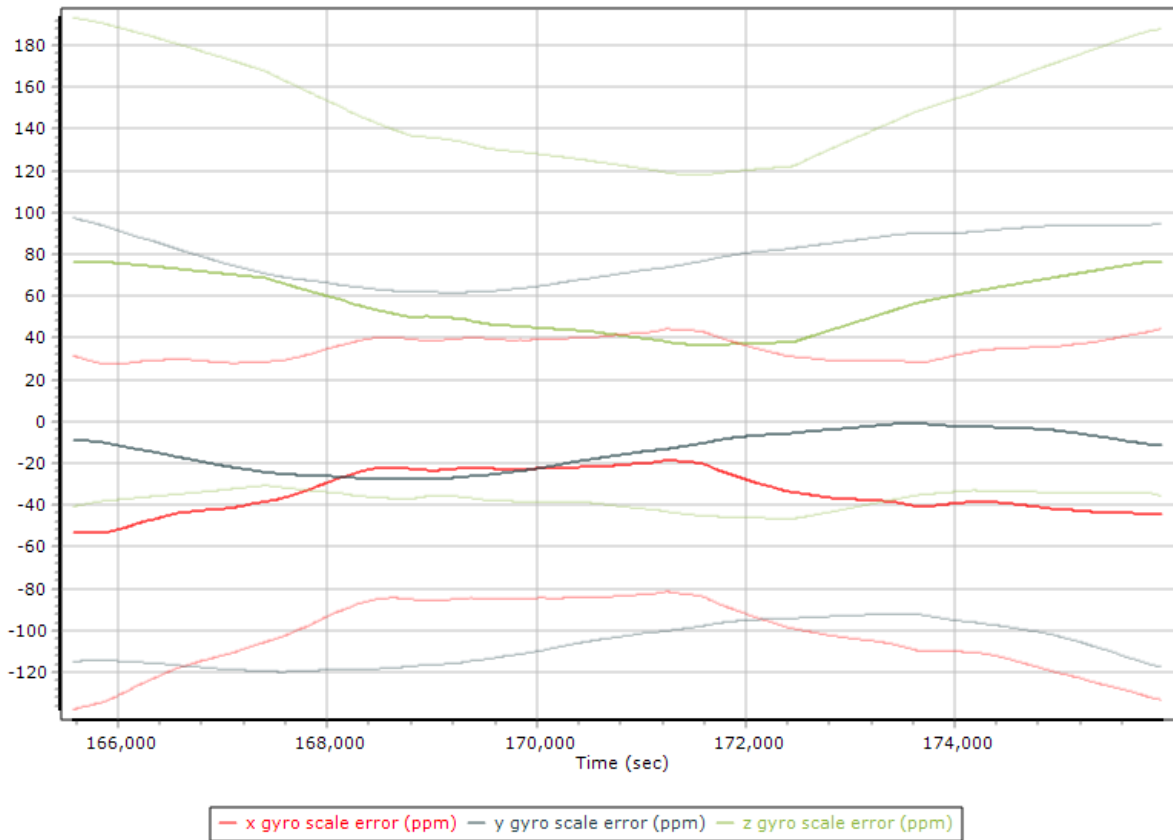












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

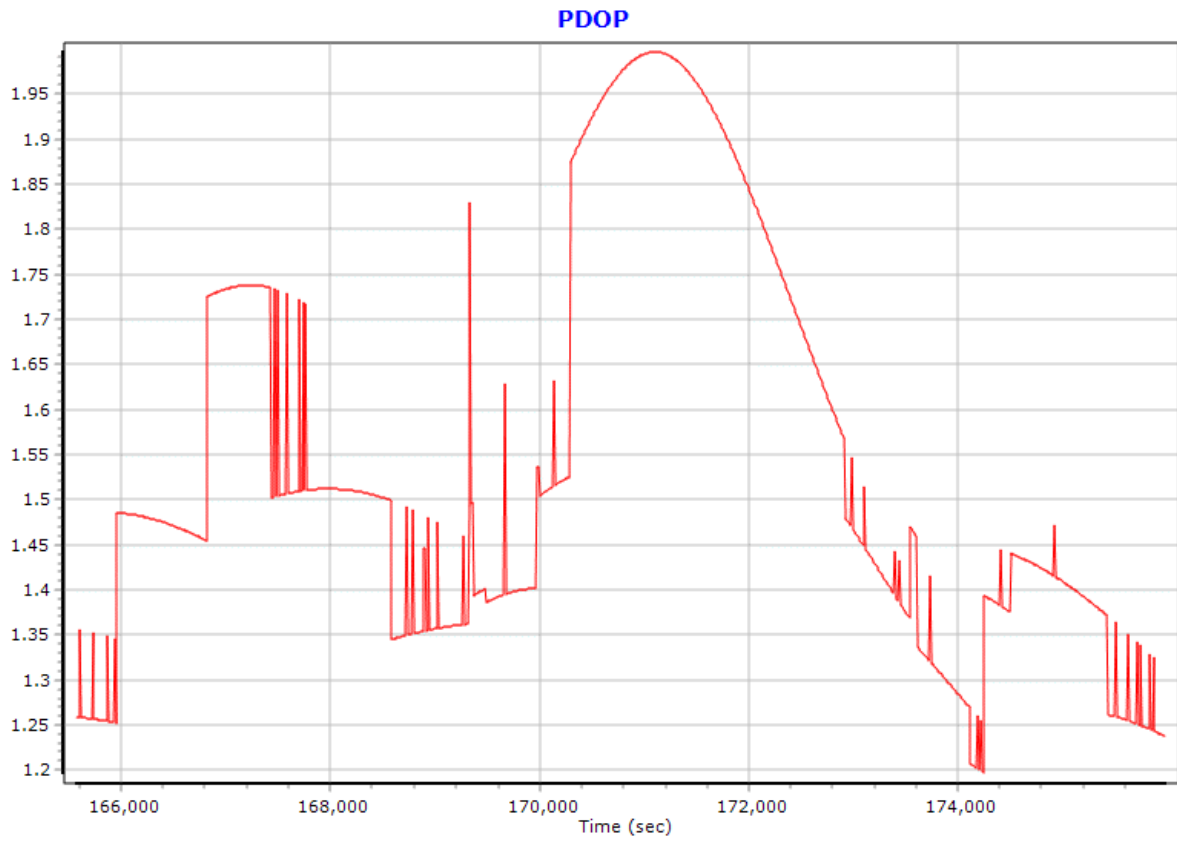
Standard Deviation: 3cm 10cm 50cm 1m 10m

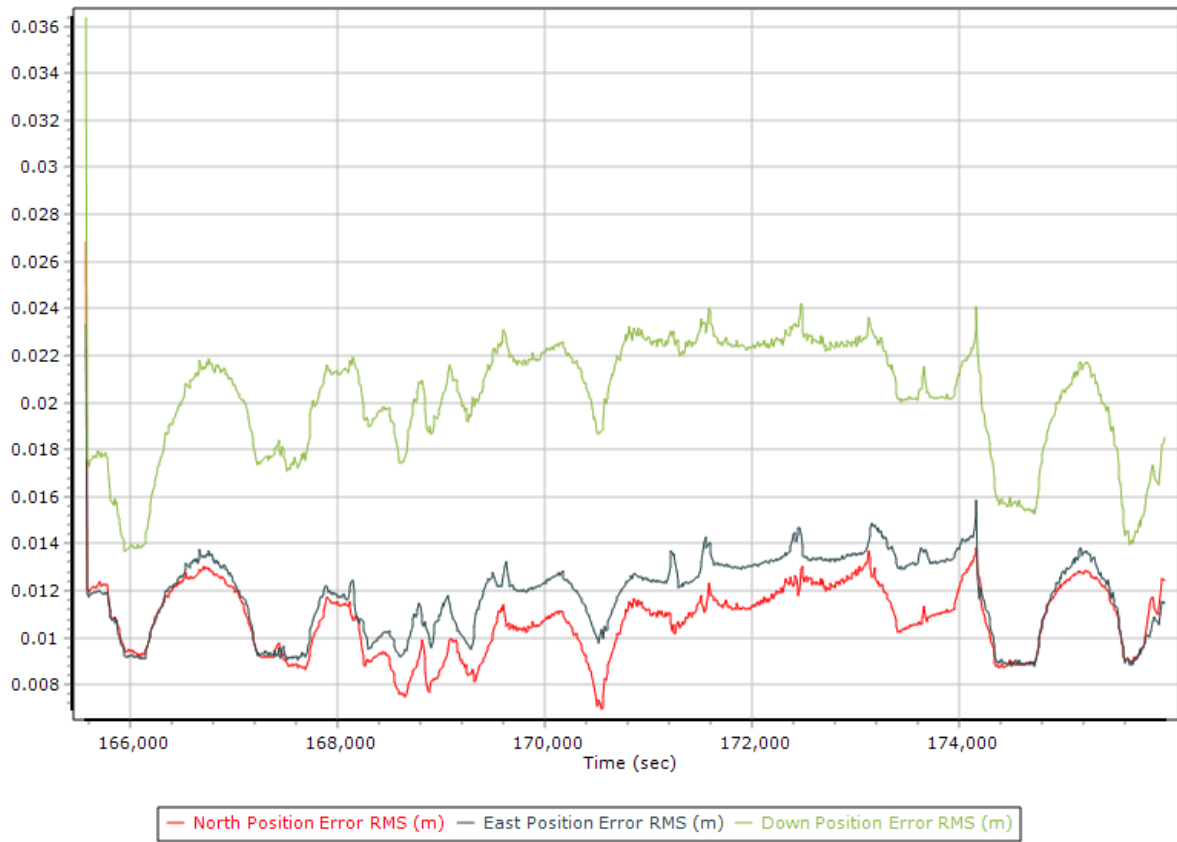
Aircraft to Reference Mounting Angles

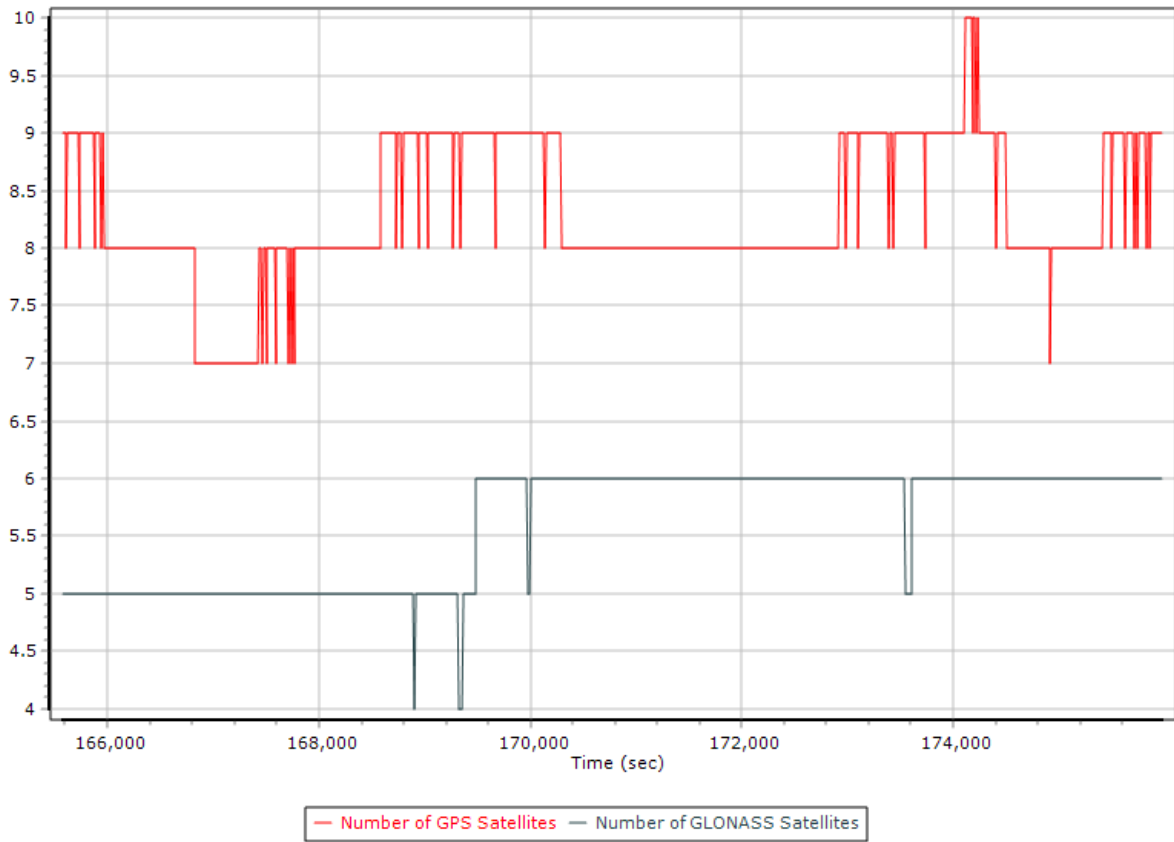
X:

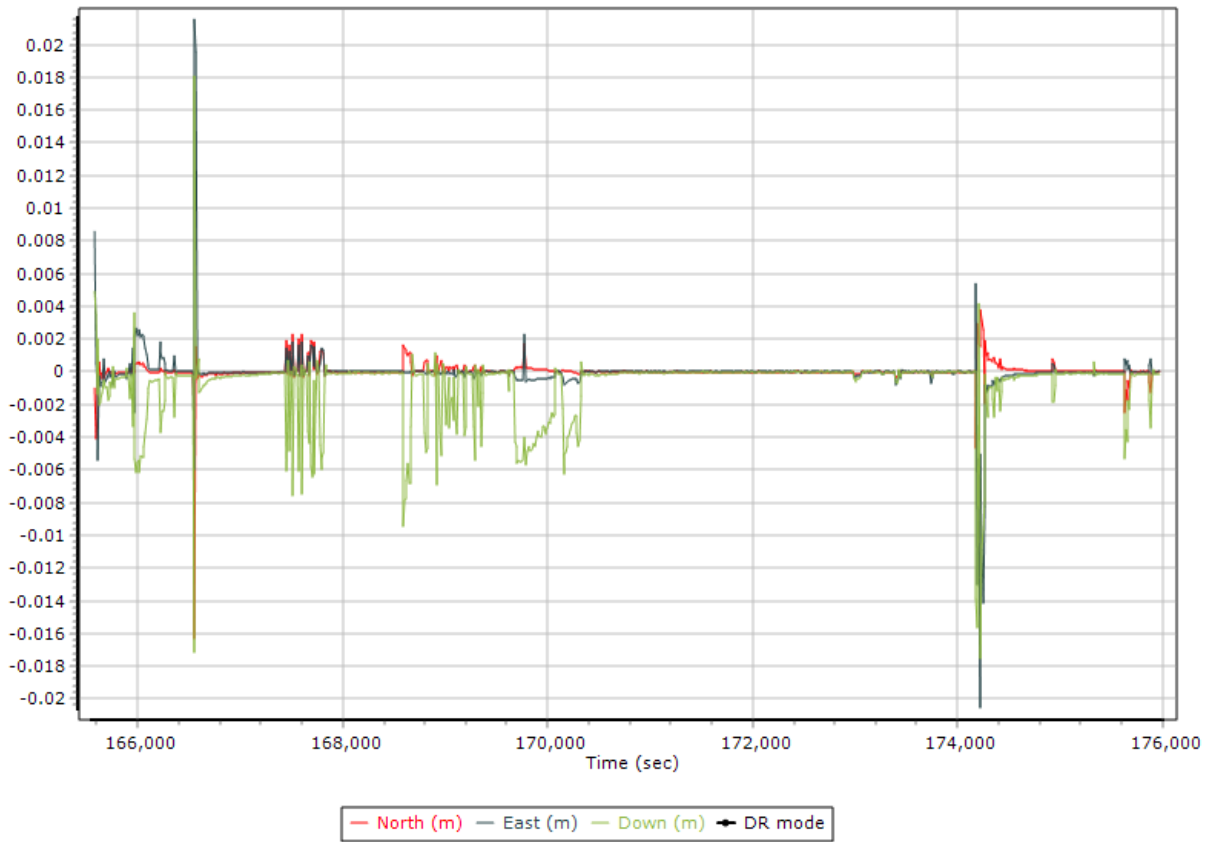
Y:

Z:









Project Settings [X]

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

Timing

Start: 165001.000
 End: 175990.000

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

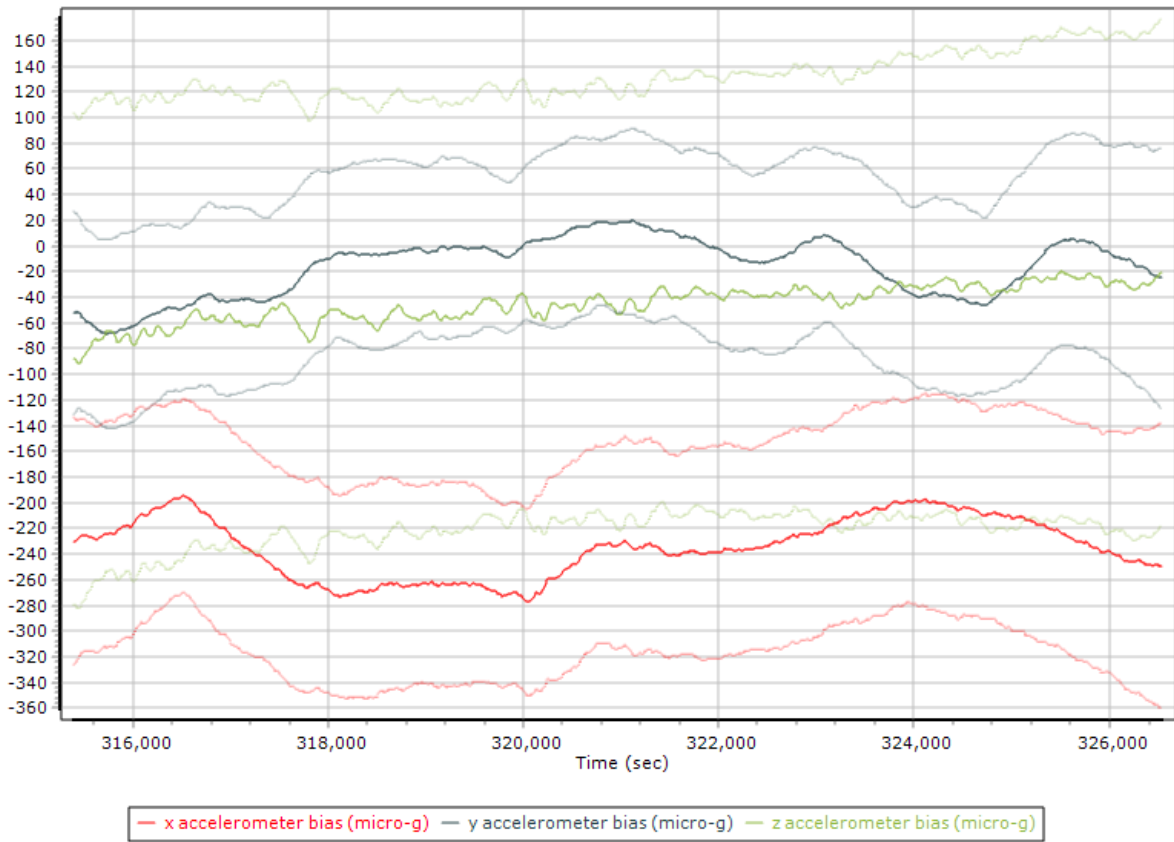
Processable Time Windows

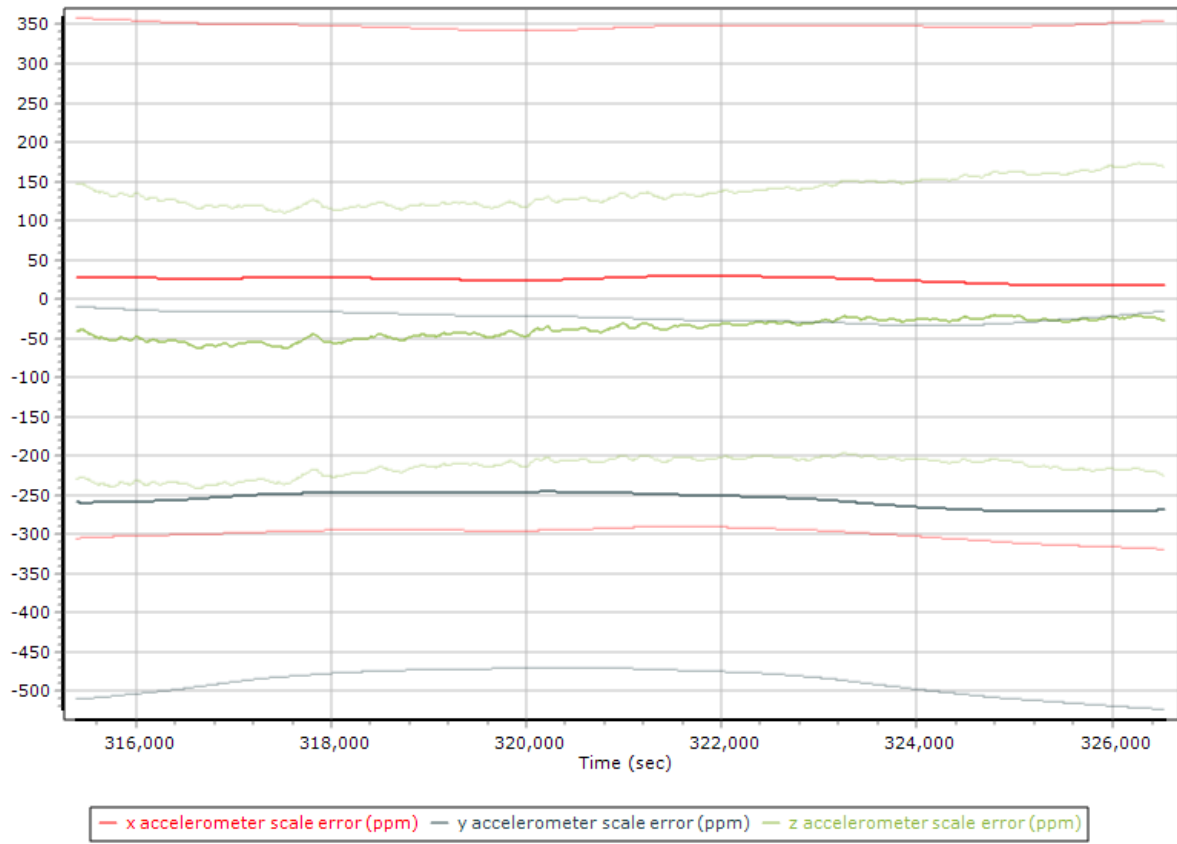
Start after launch Wait Time: 4.000 sec

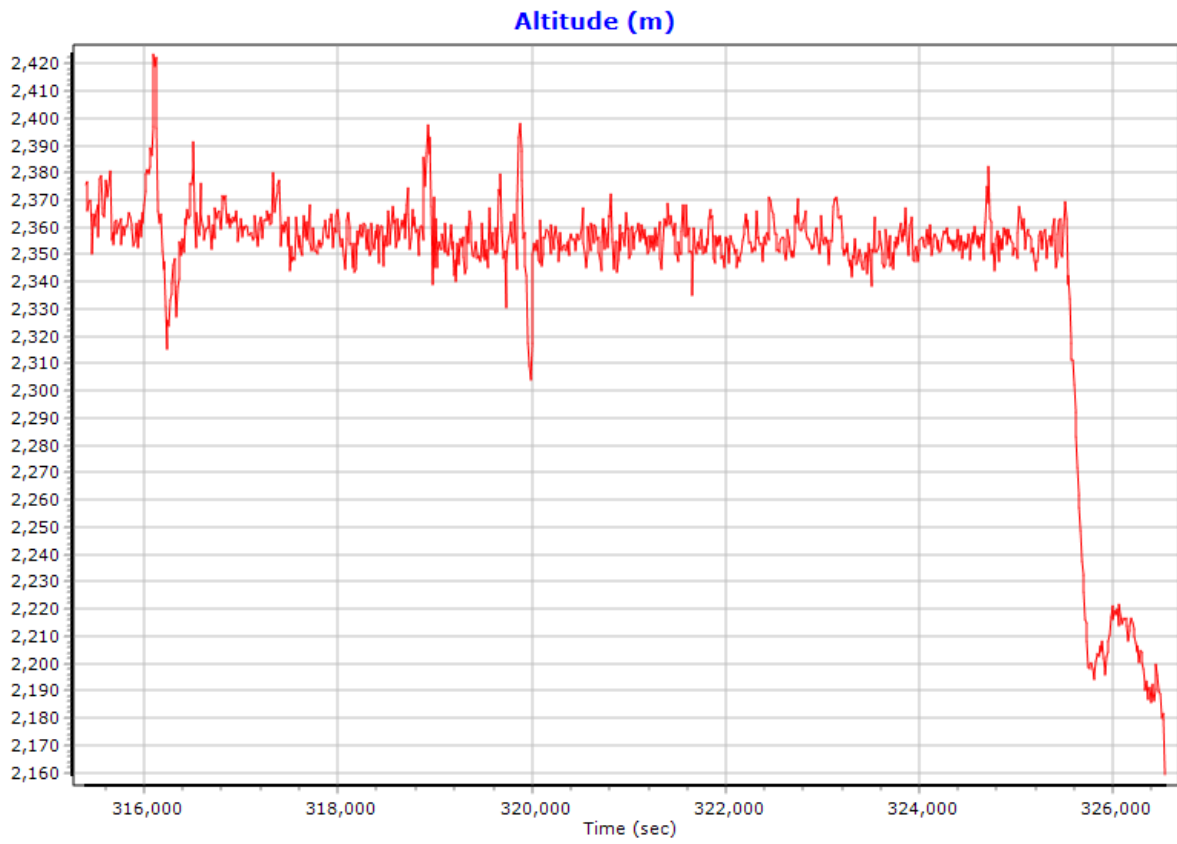
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	165001.000	175990.000	10989.000	End of file

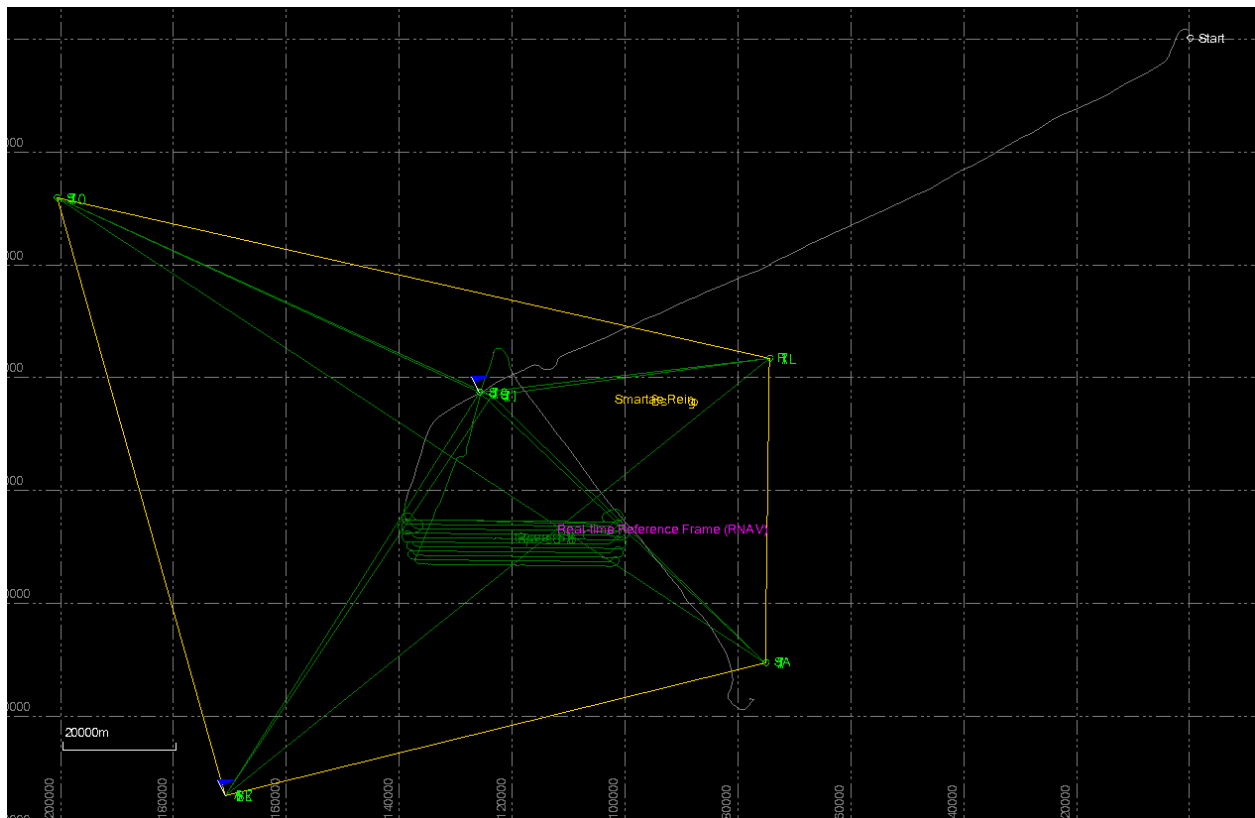
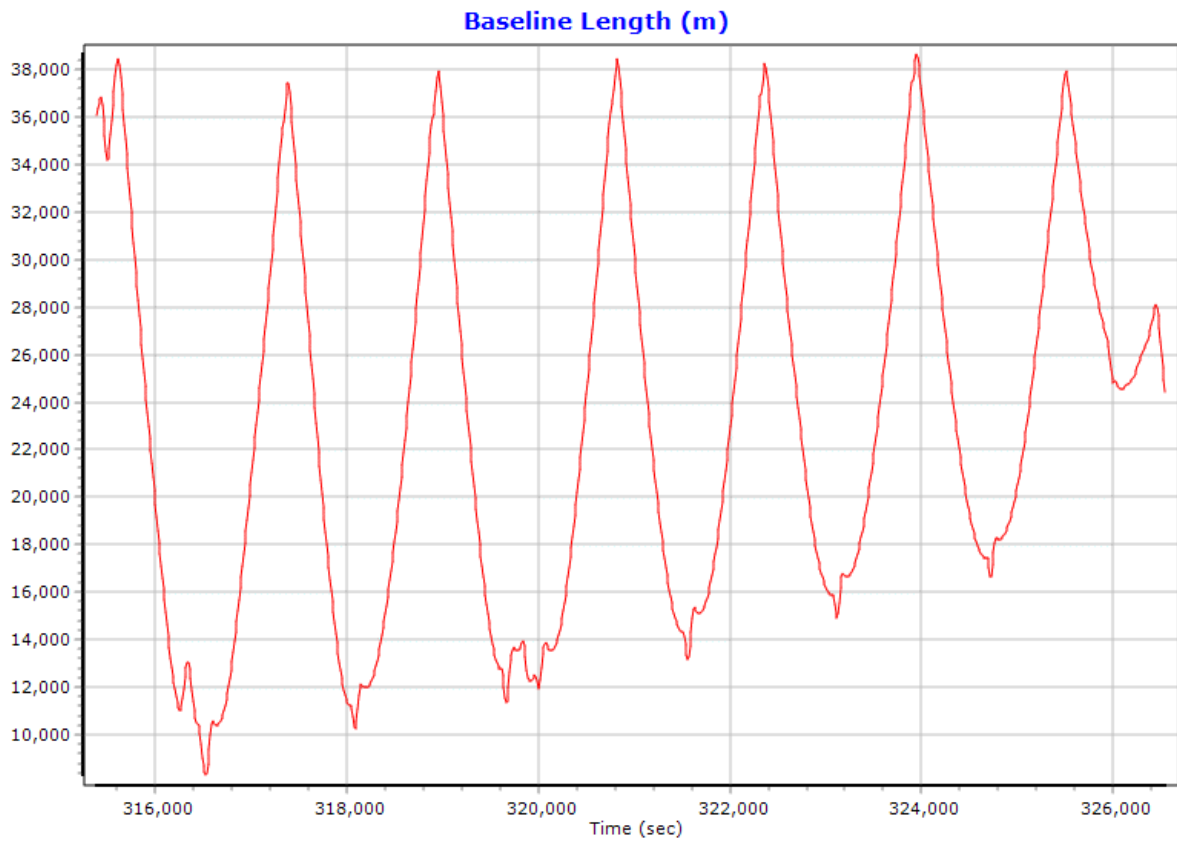
OK Cancel

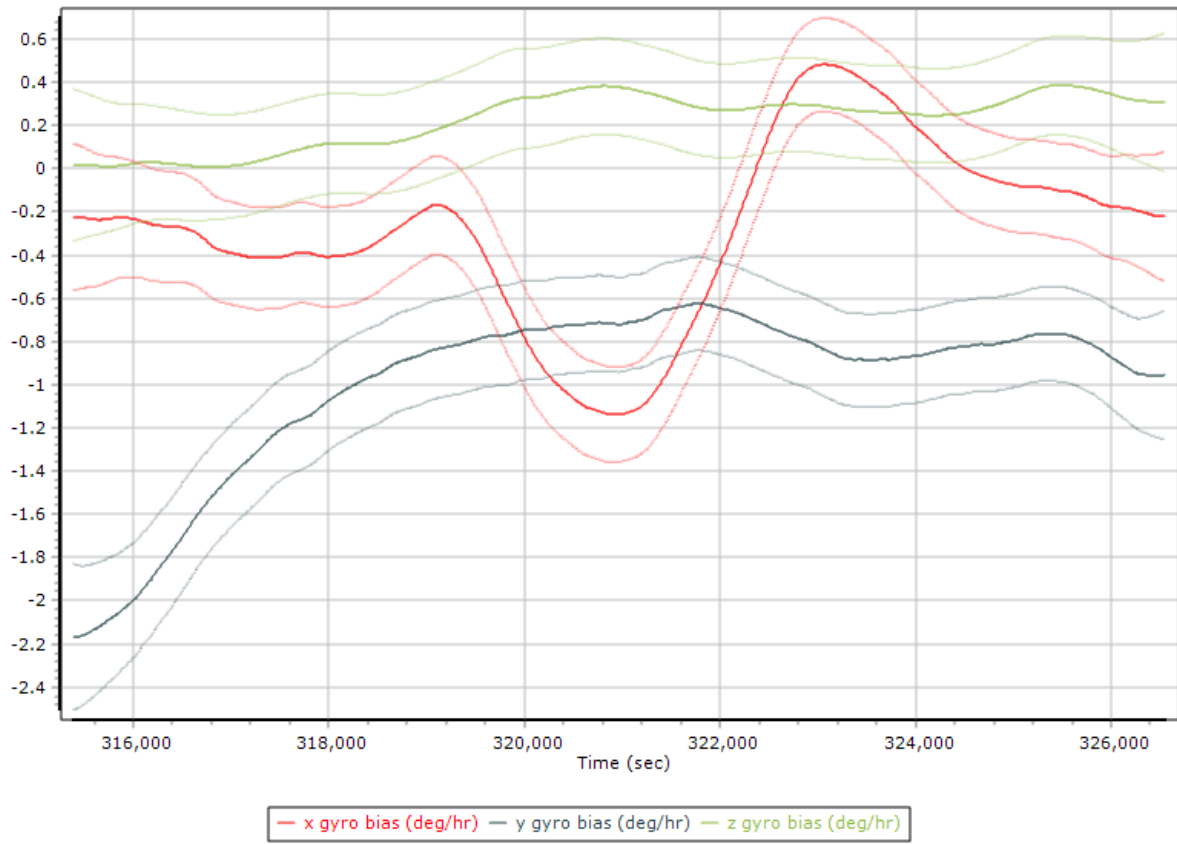
CAU18038A

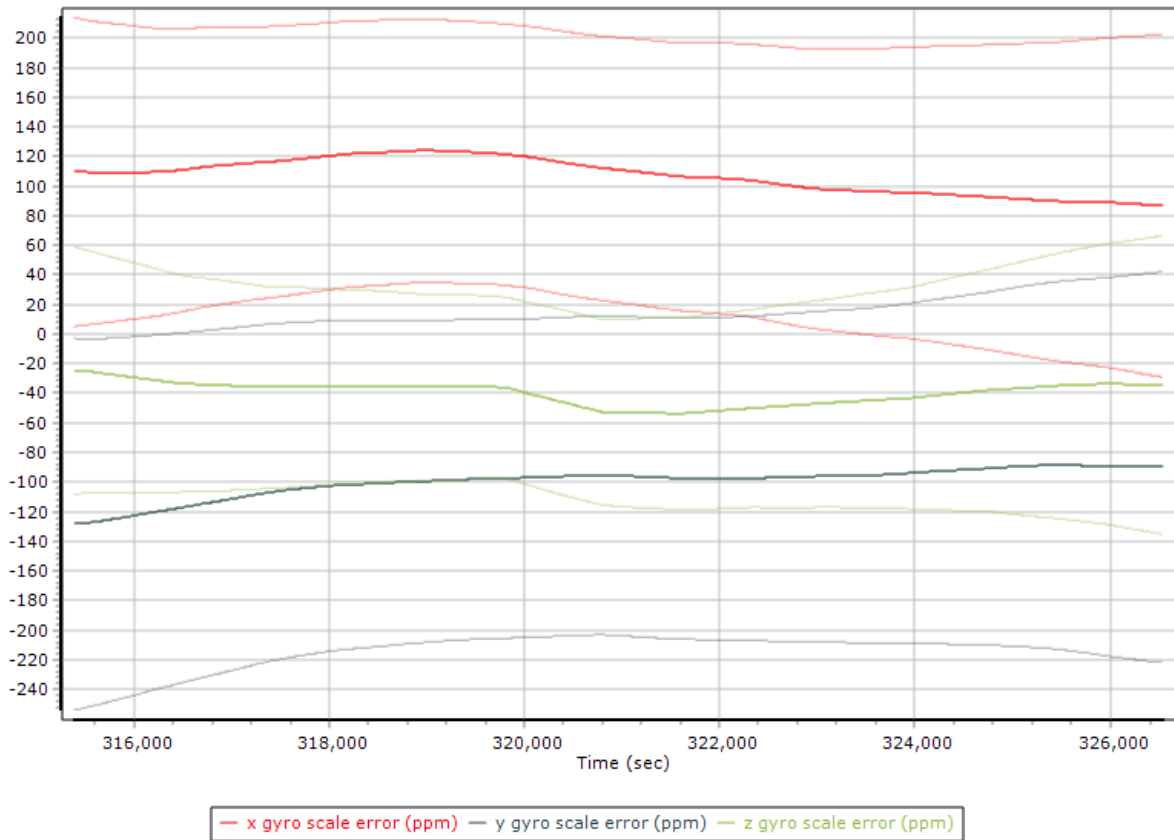












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

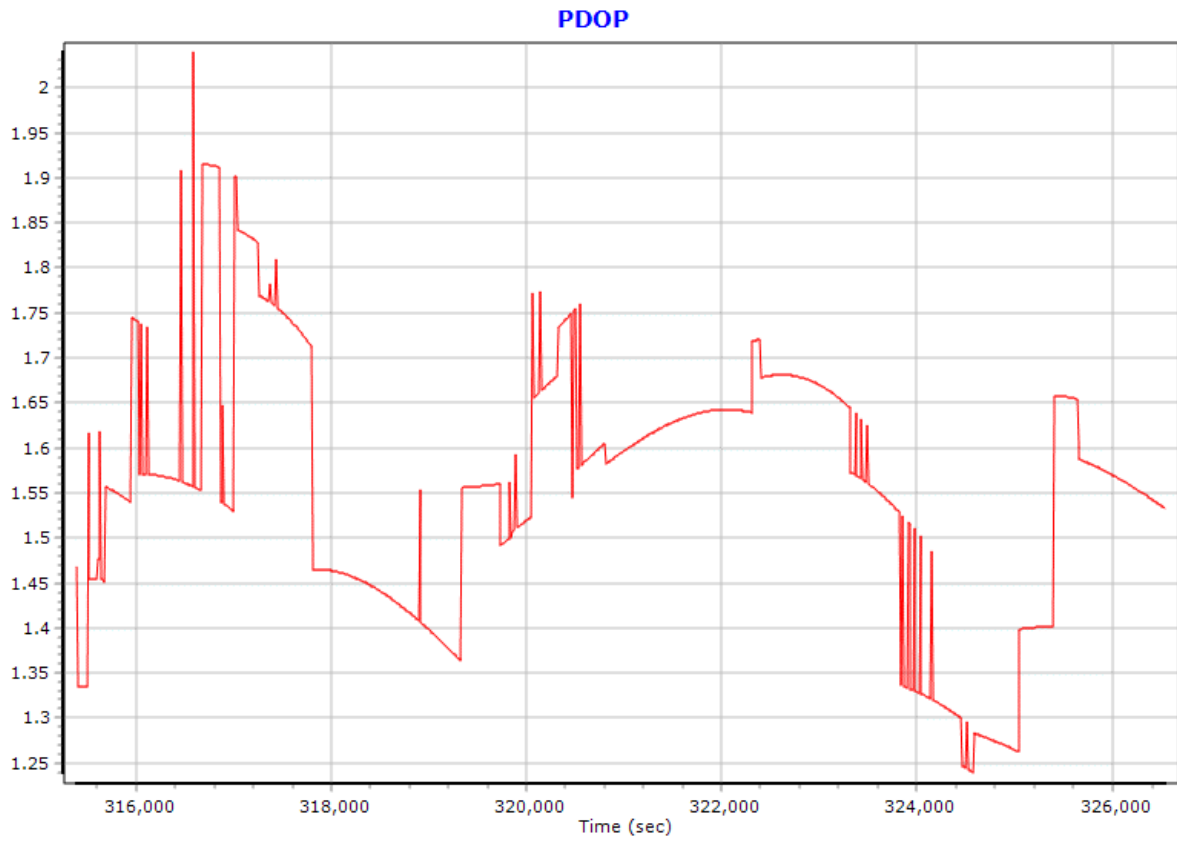
<3cm 10cm 50cm 1m 10m

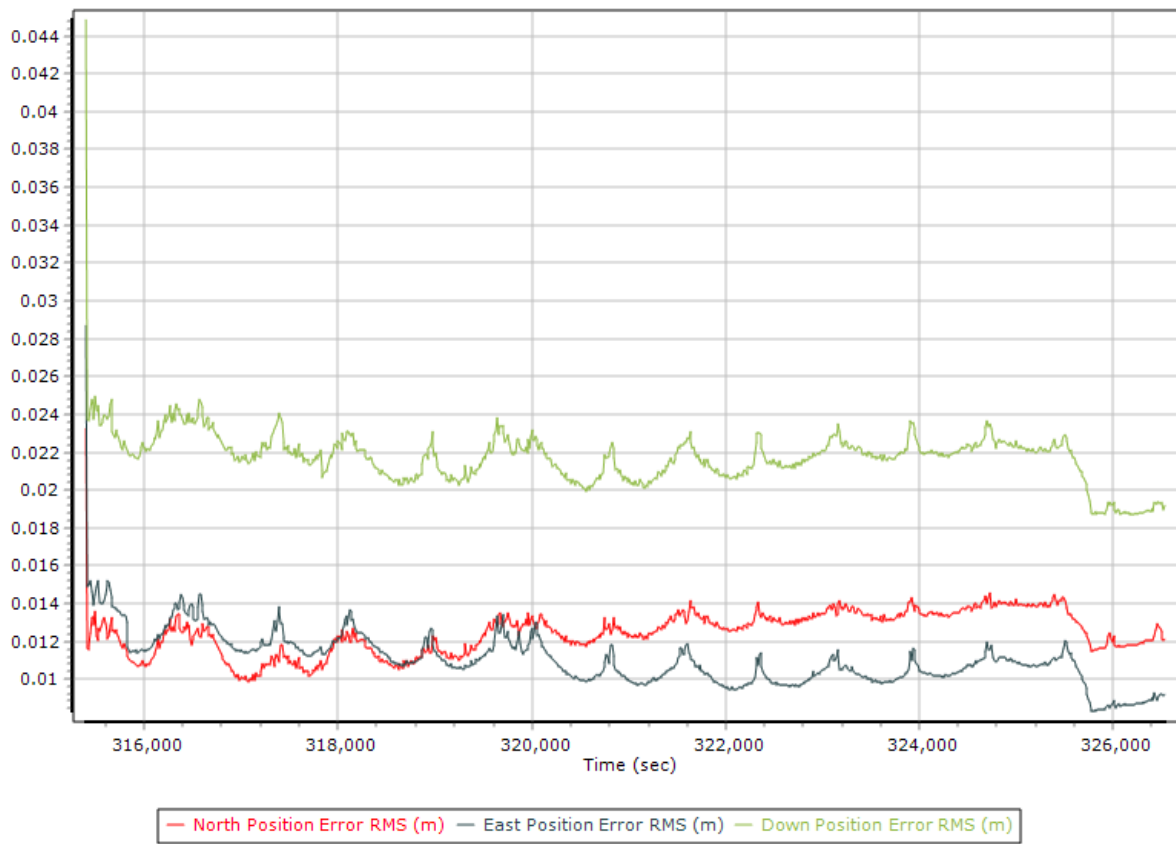
Aircraft to Reference Mounting Angles

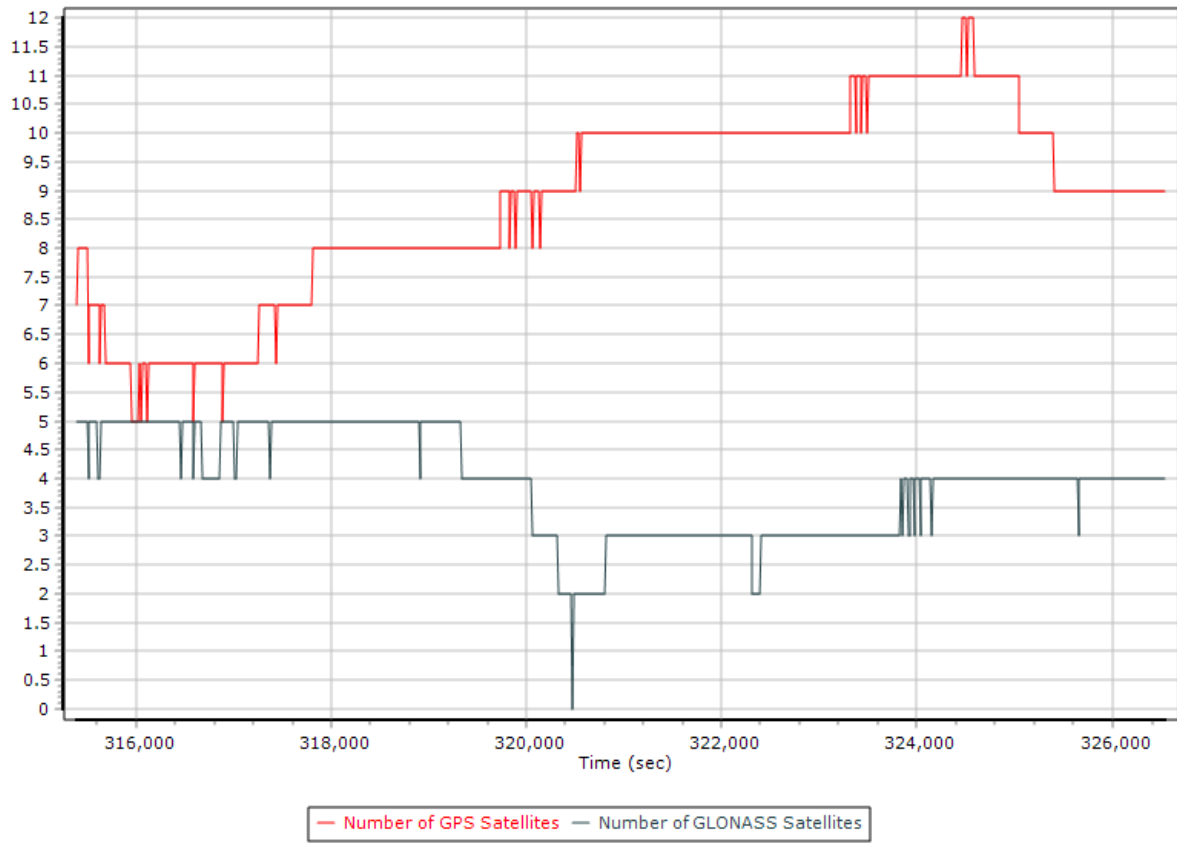
X:

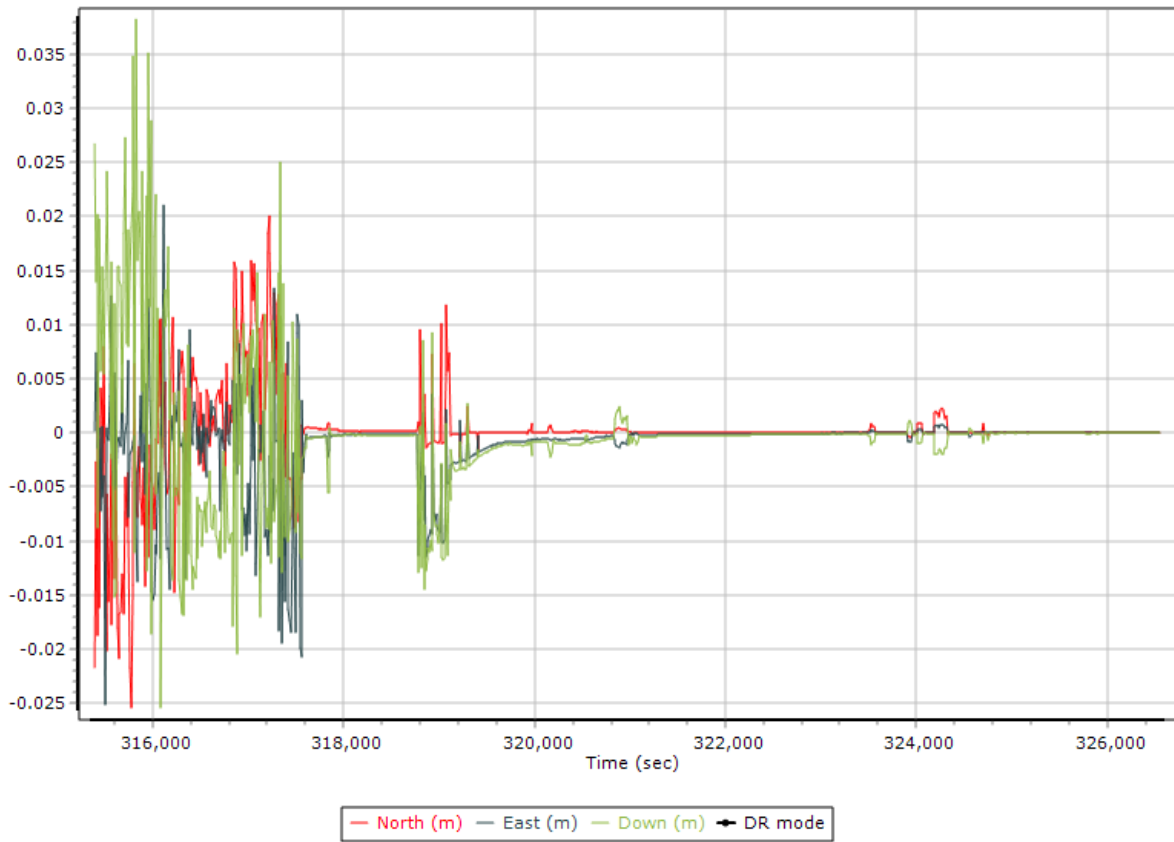
Y:

Z:









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: 311648.000
 End: 328254.000
 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

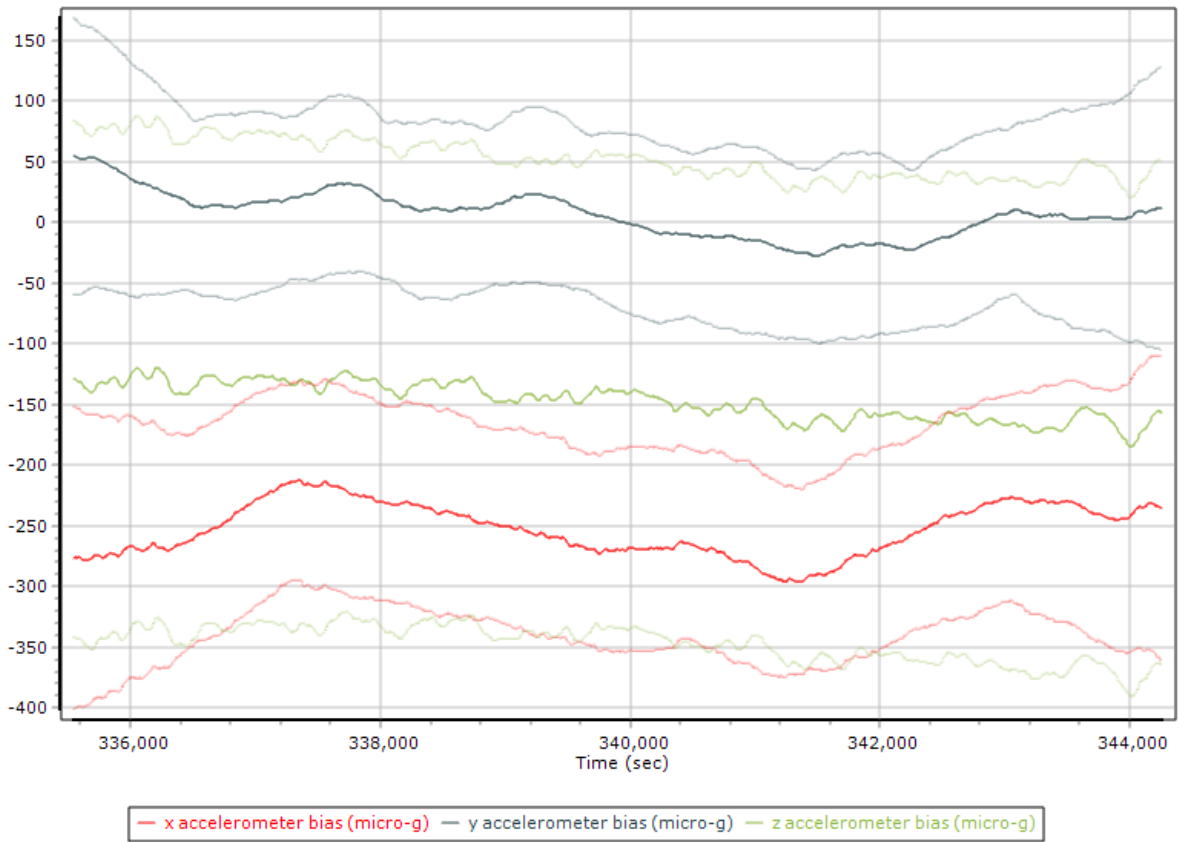
Processable Time Windows

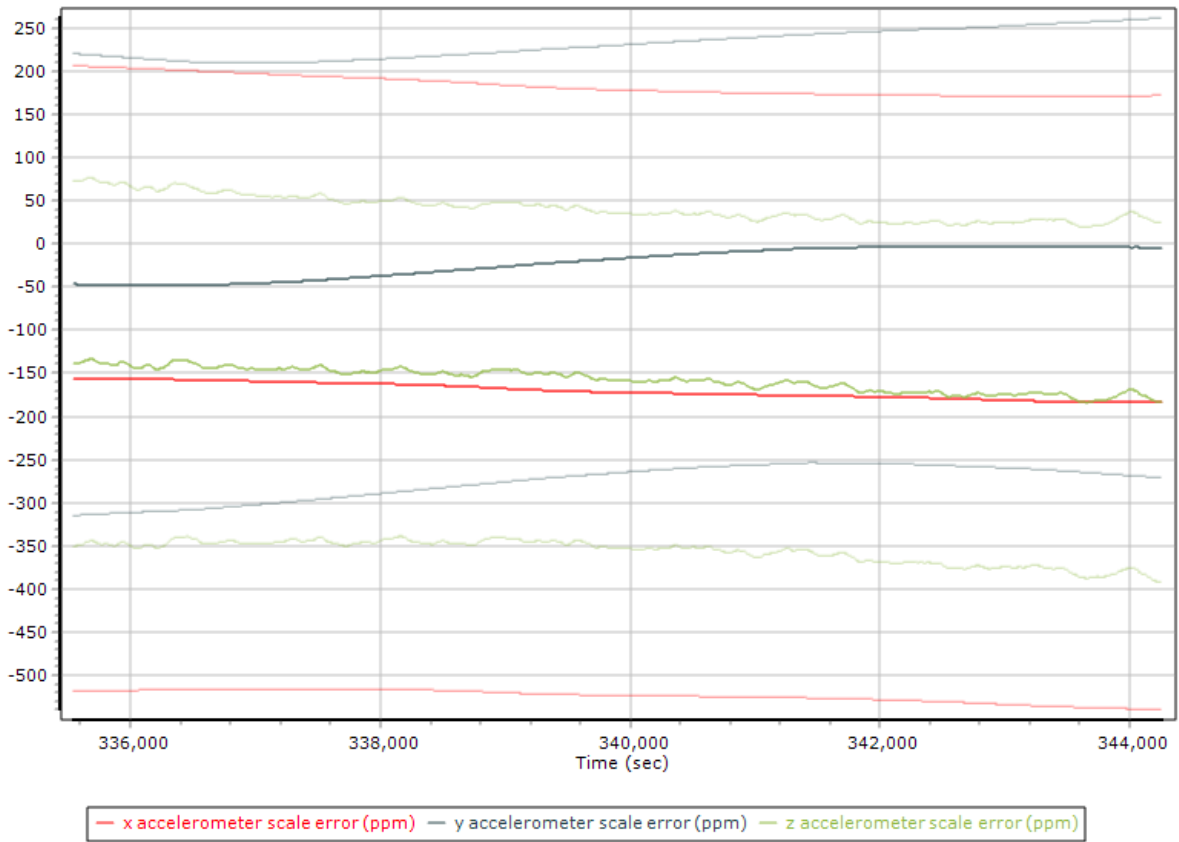
Start after launch Wait Time: 4.000 sec

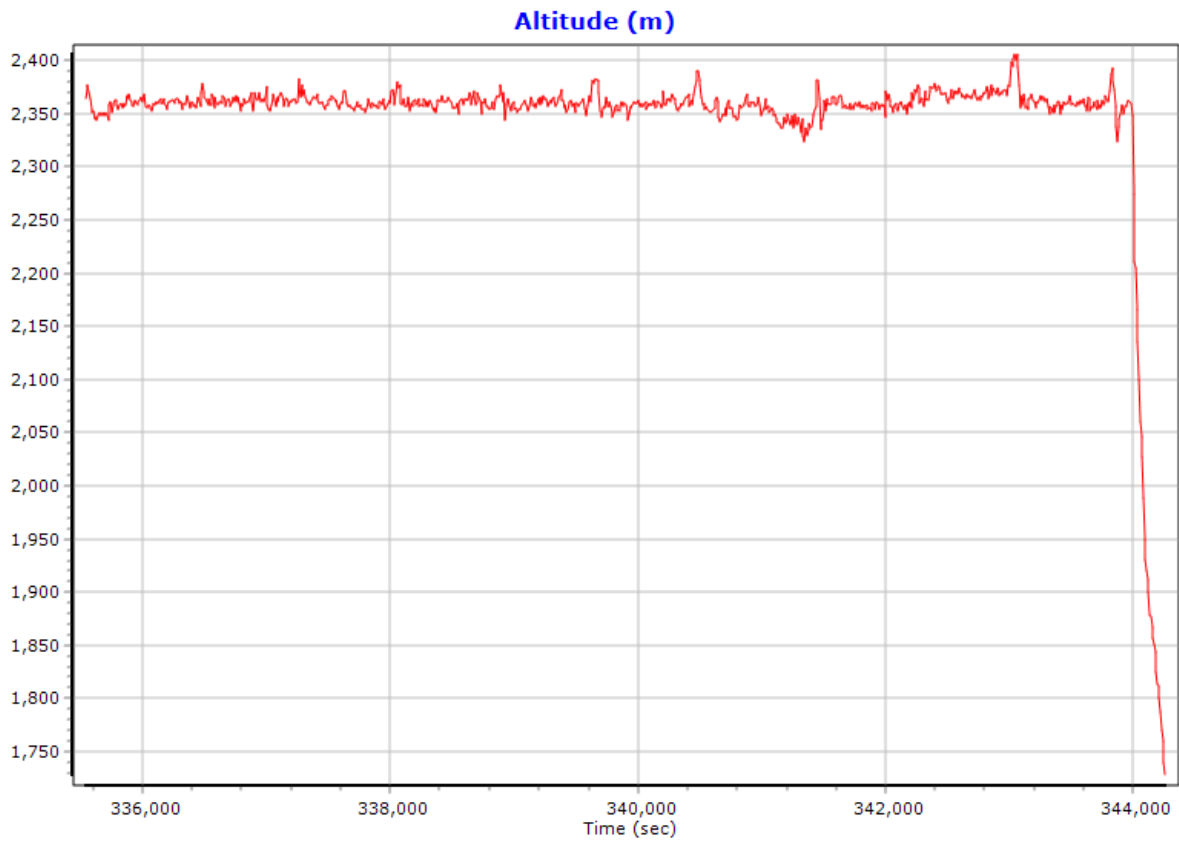
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	311648.000	328254.000	16606.000	End of file

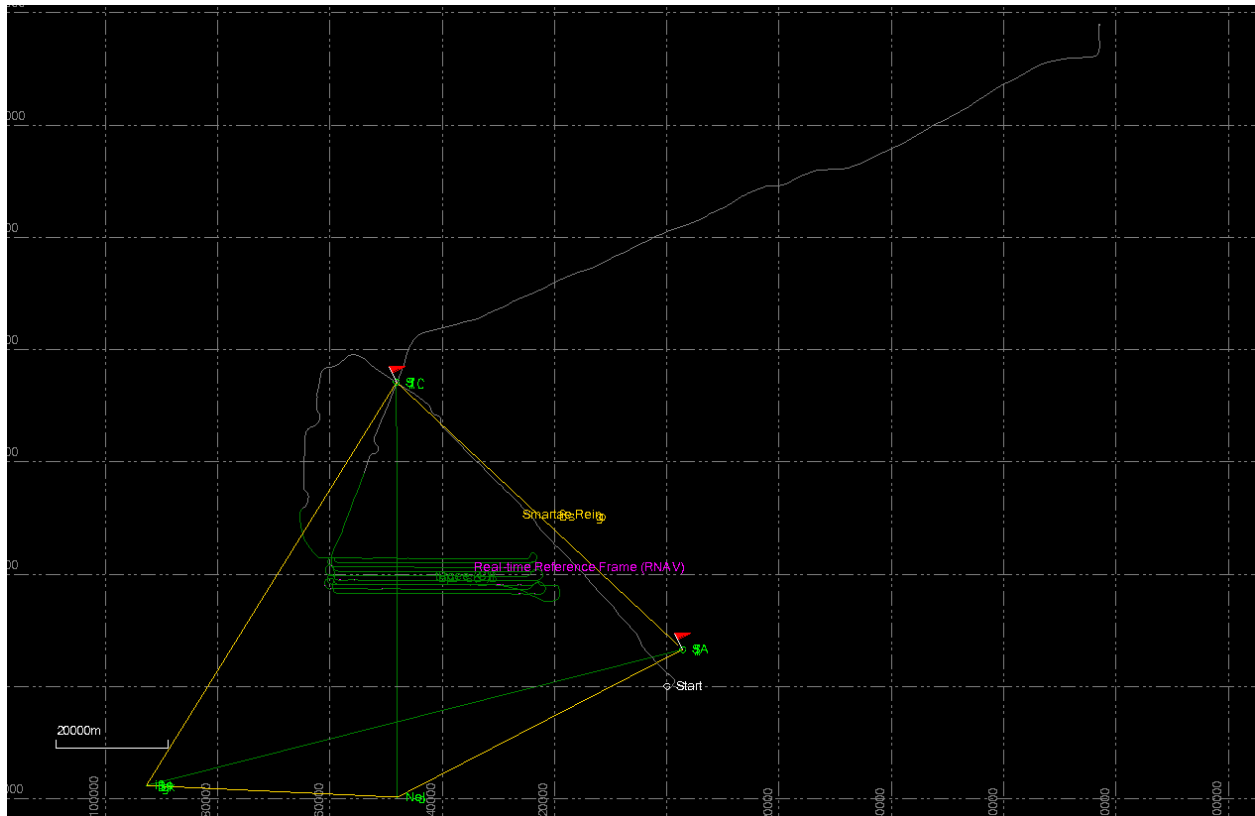
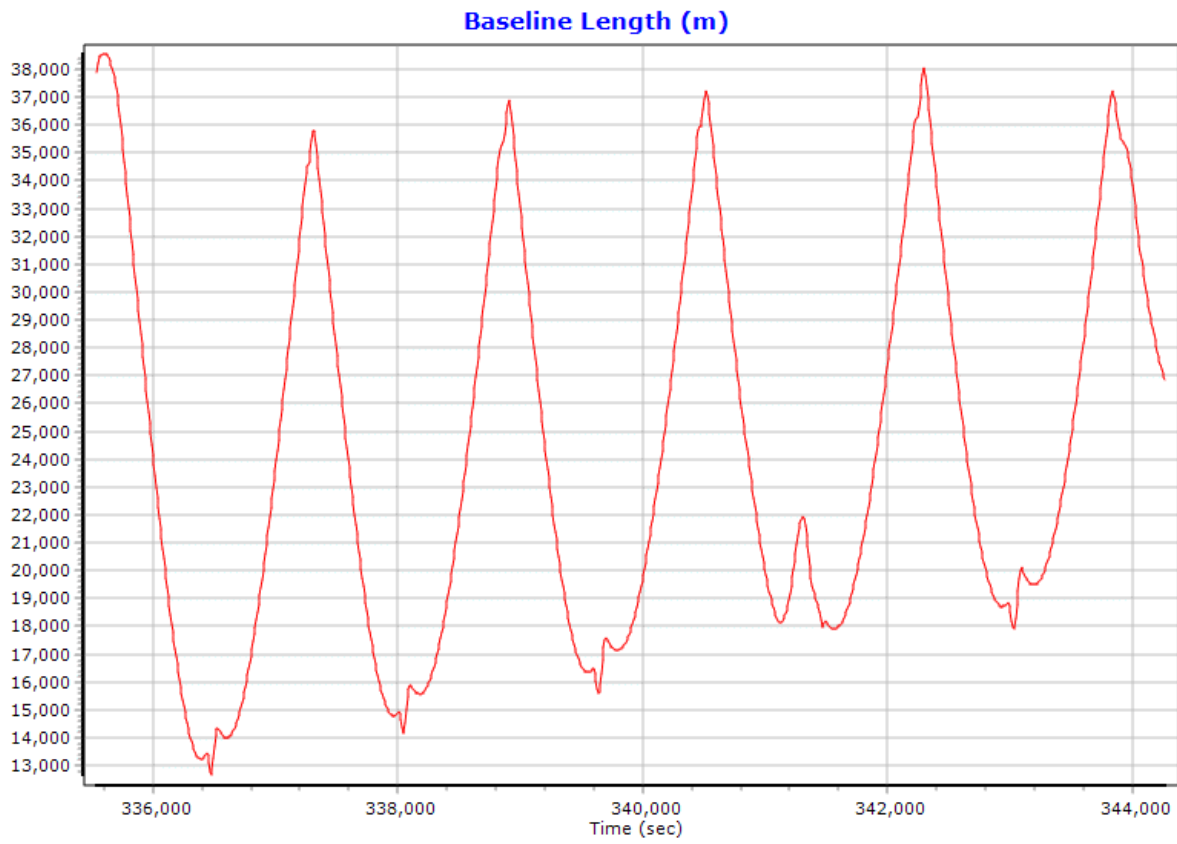
OK Cancel

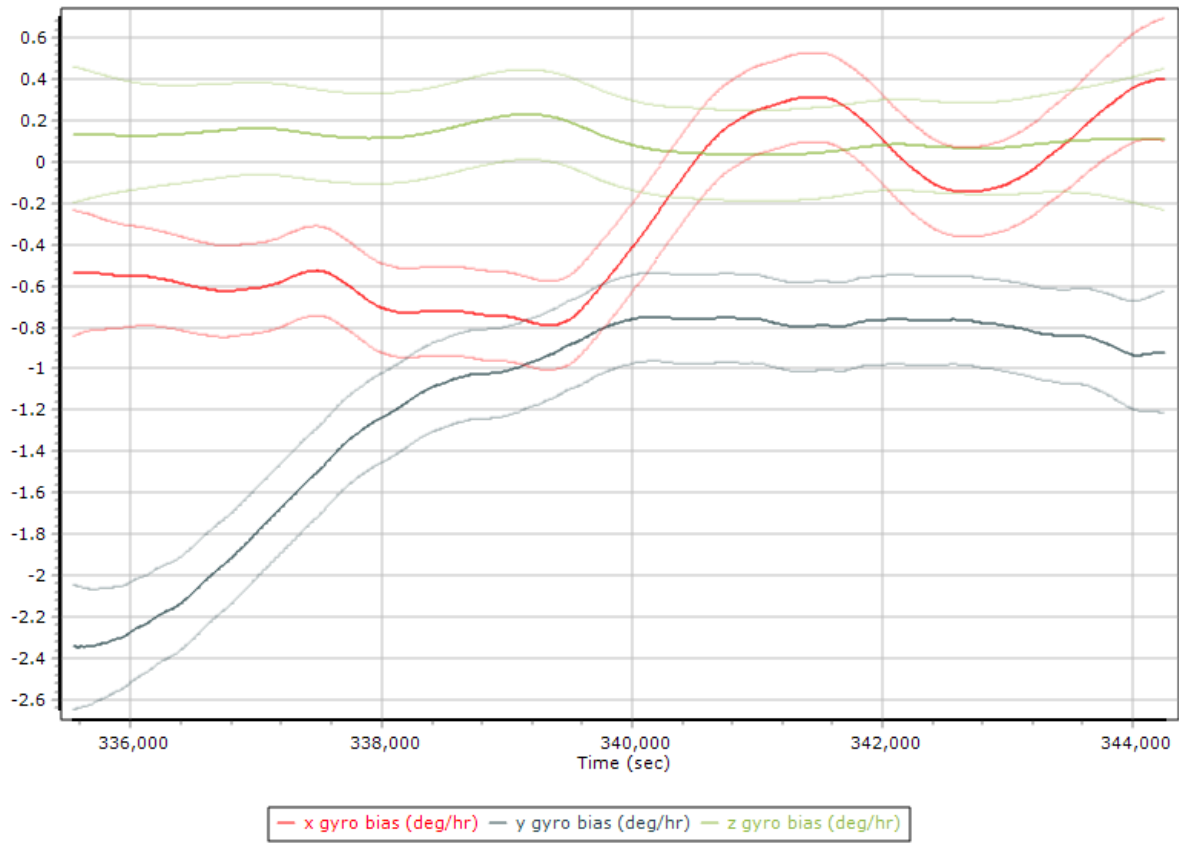
CAU18038B

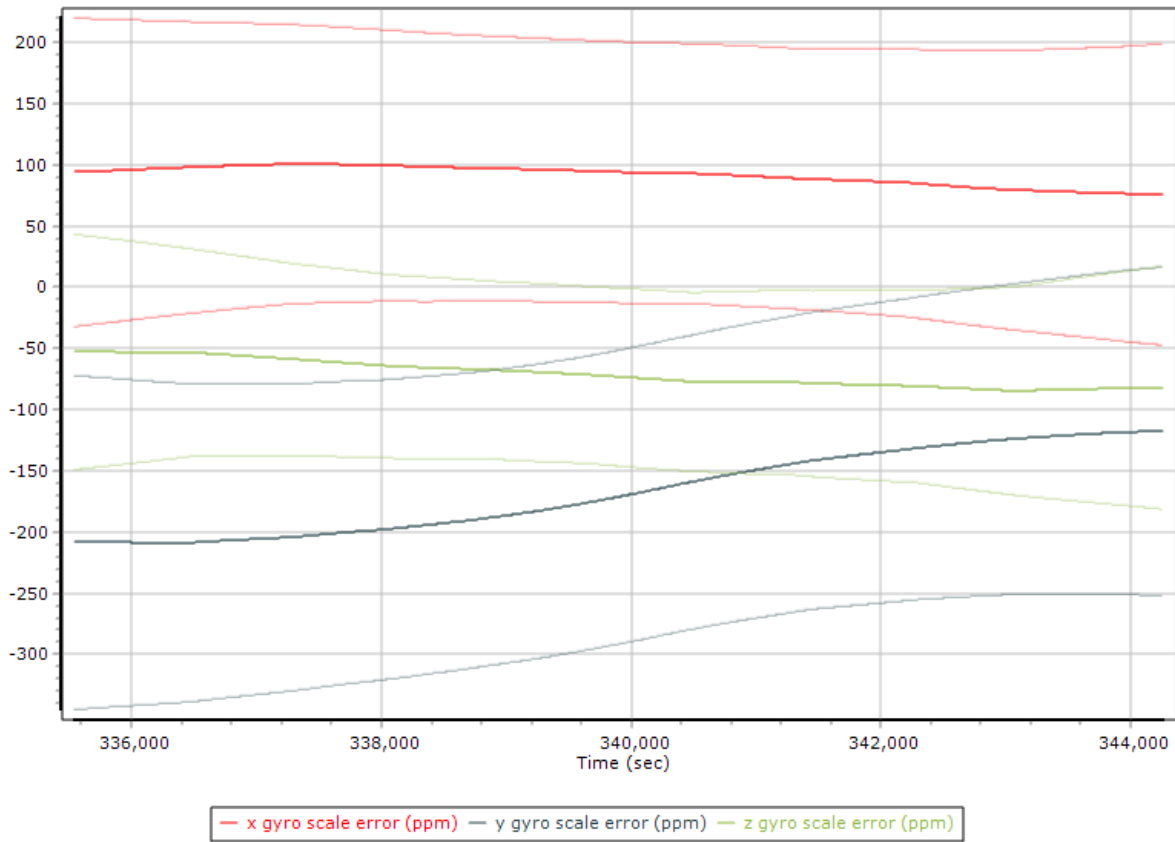












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

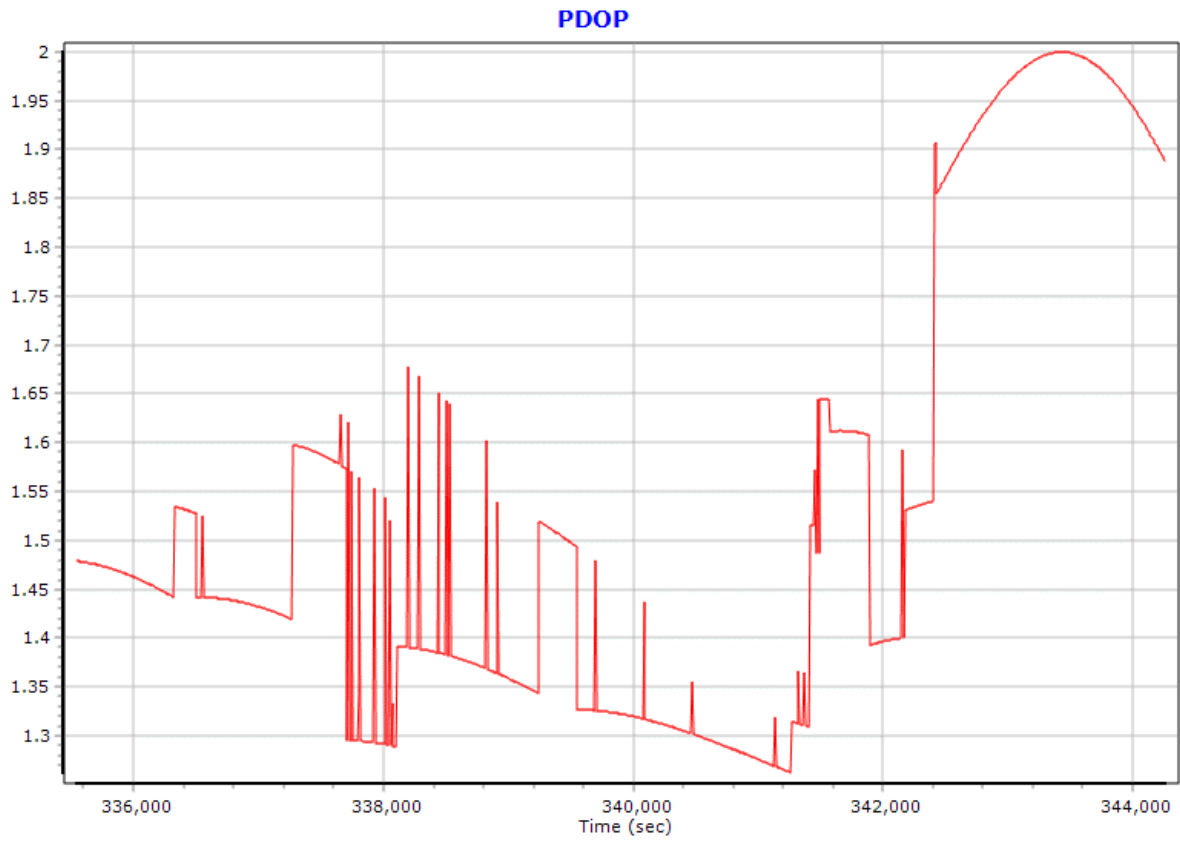
Aircraft to Reference Mounting Angles

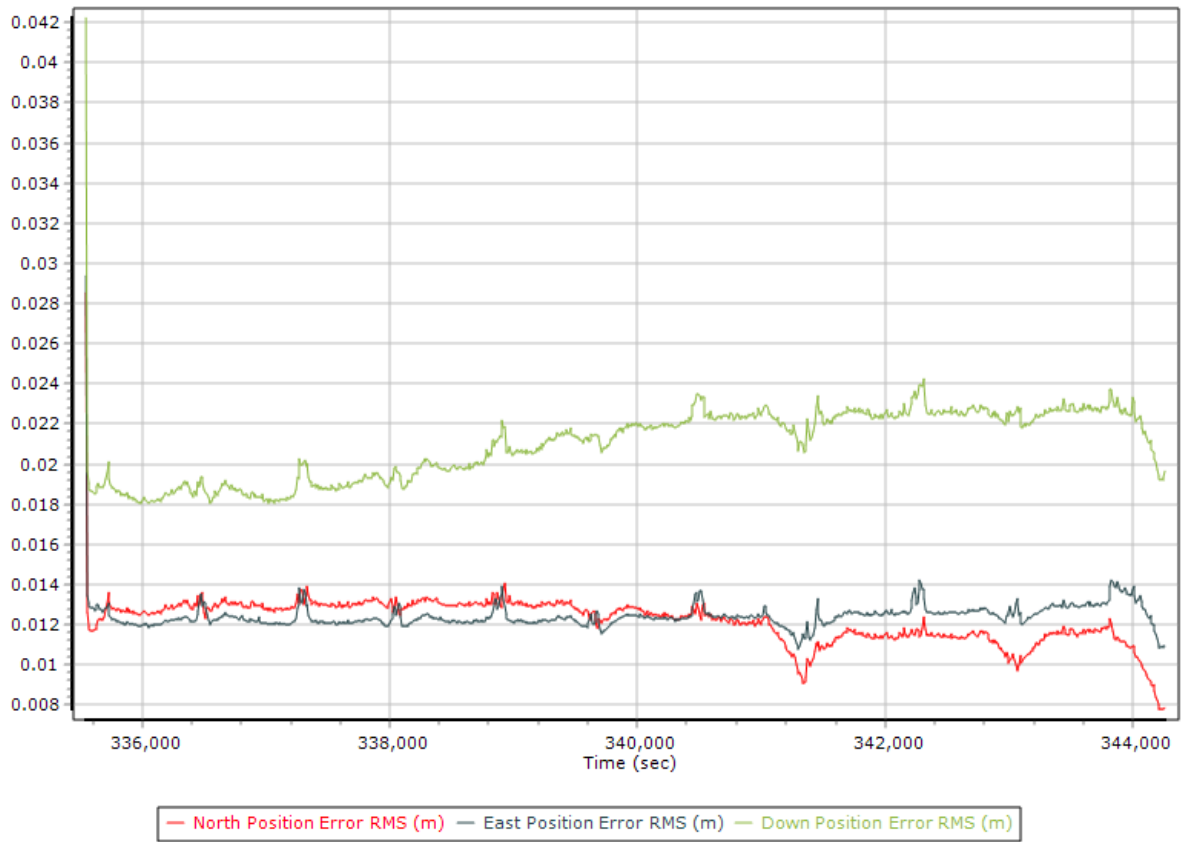
X:

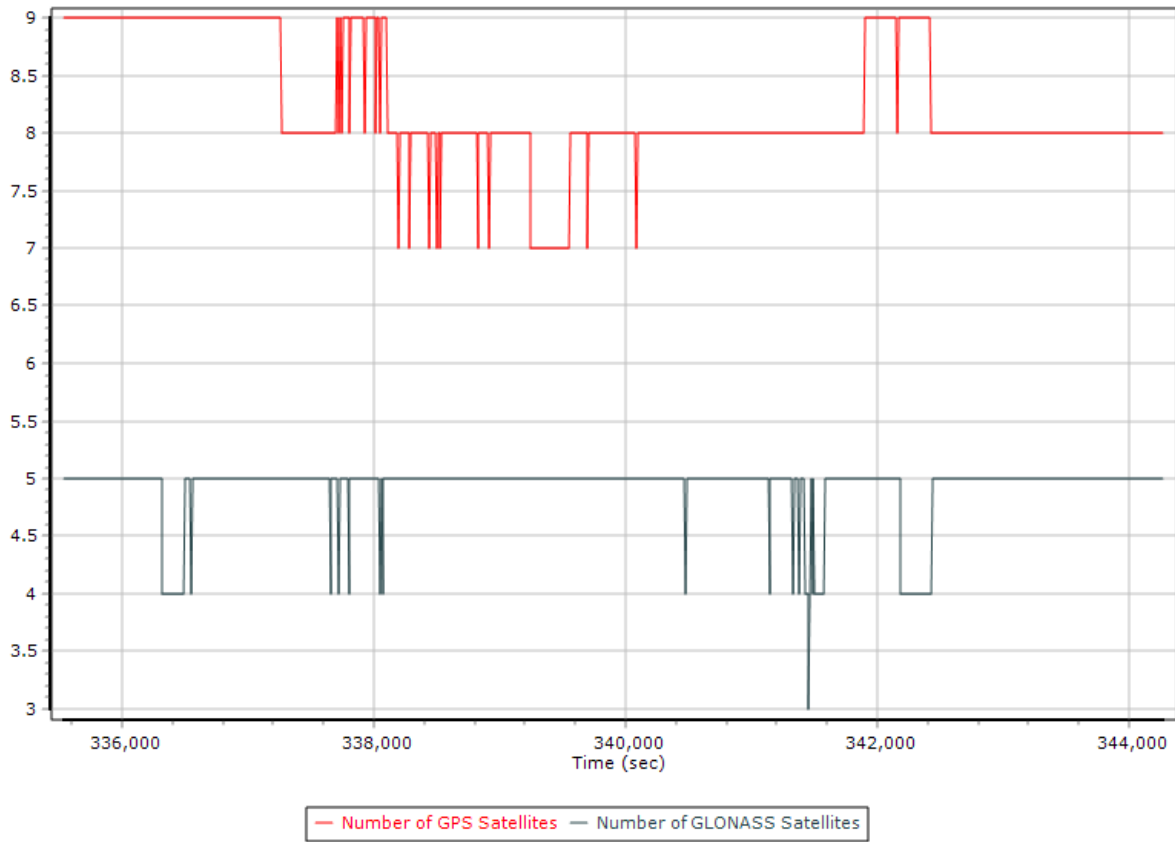
Y:

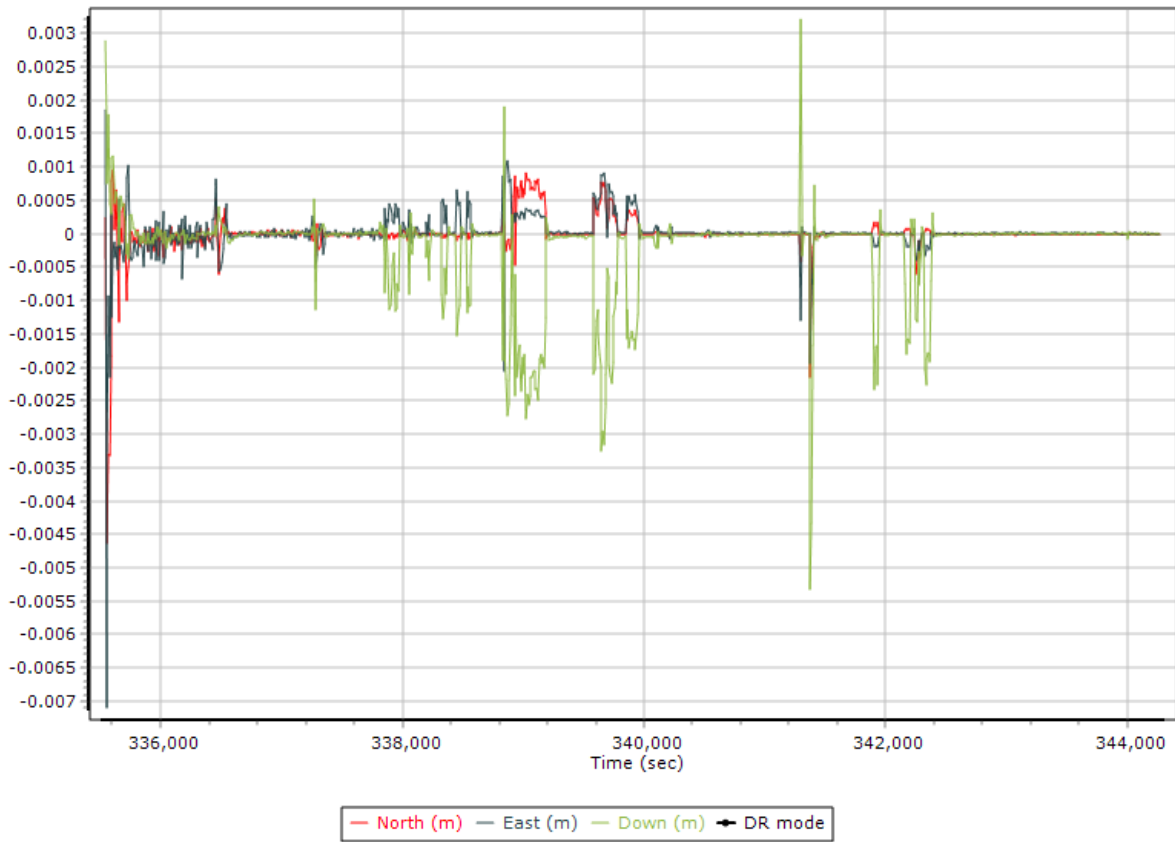
Z:

OK Cancel









Project Settings

- 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: 332529.000
 End: 347770.000

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

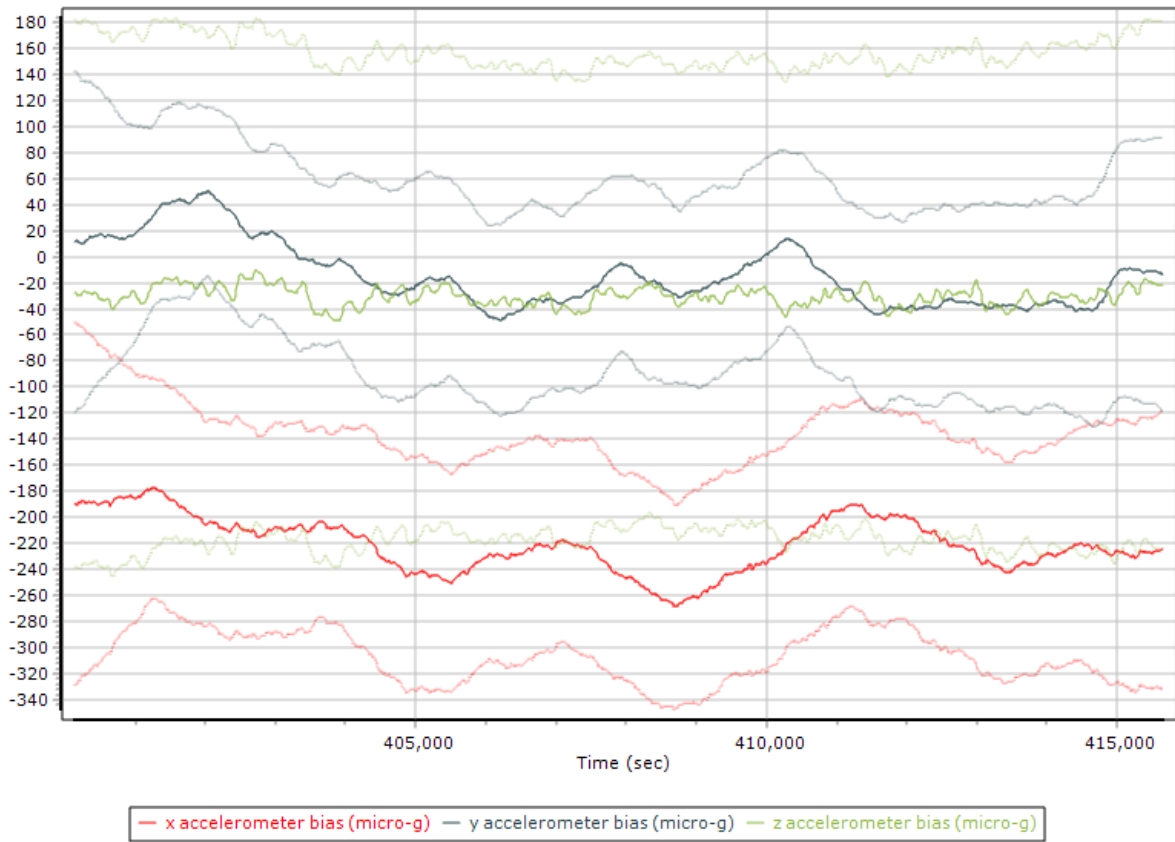
Processable Time Windows

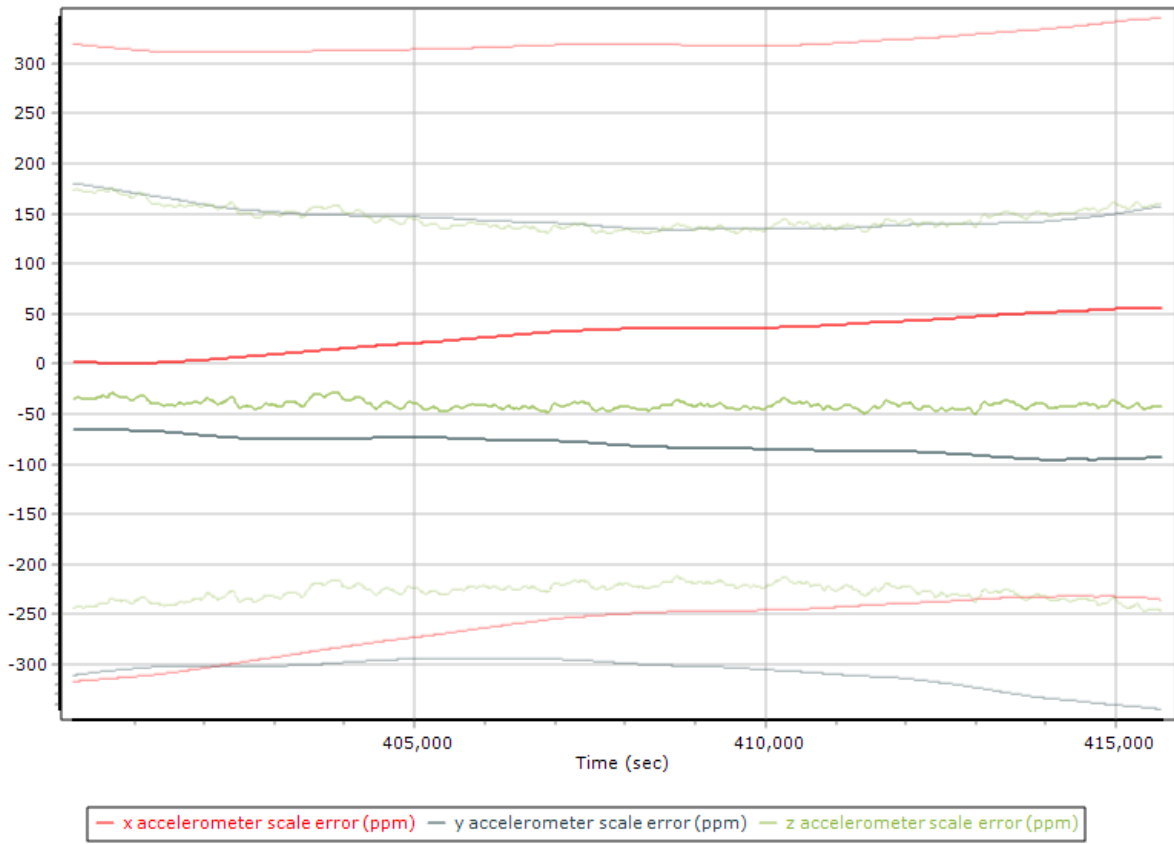
Start after launch Wait Time: 4.000 sec

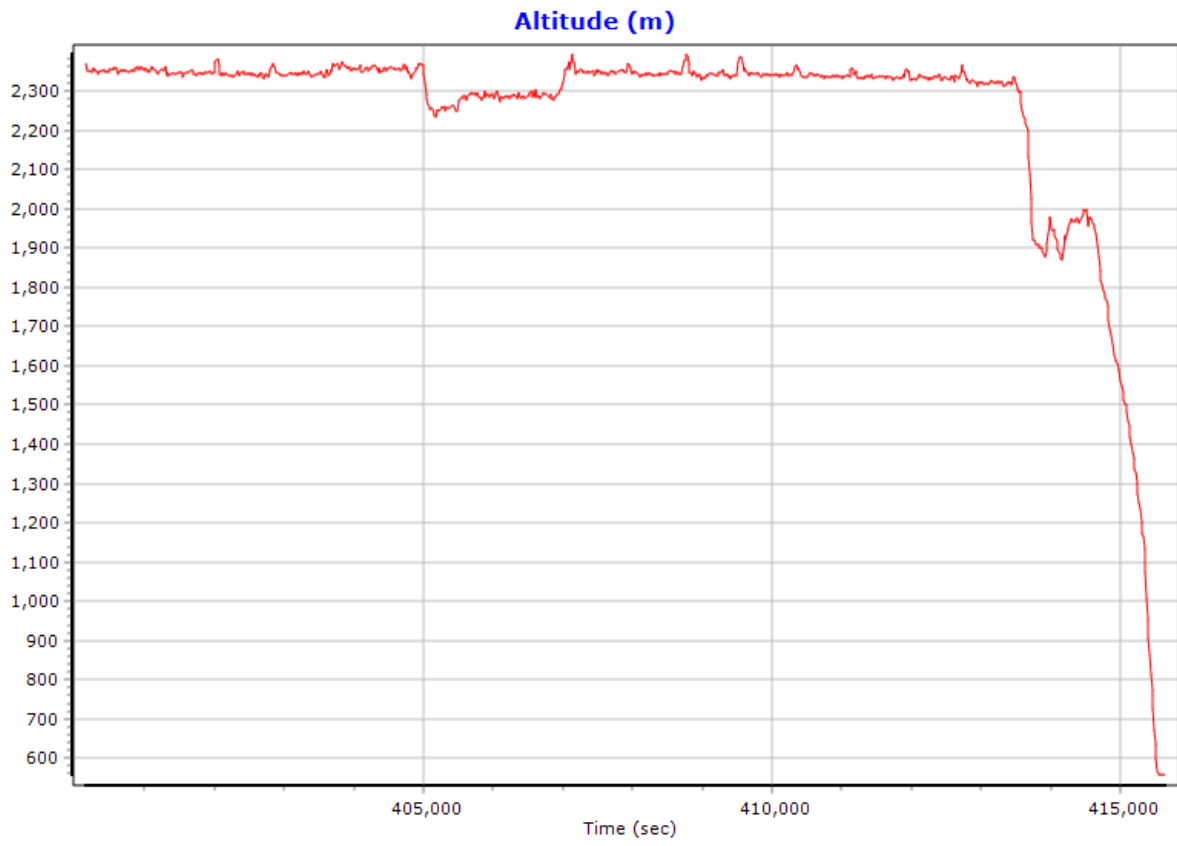
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	332529.000	347770.000	15241.000	End of file

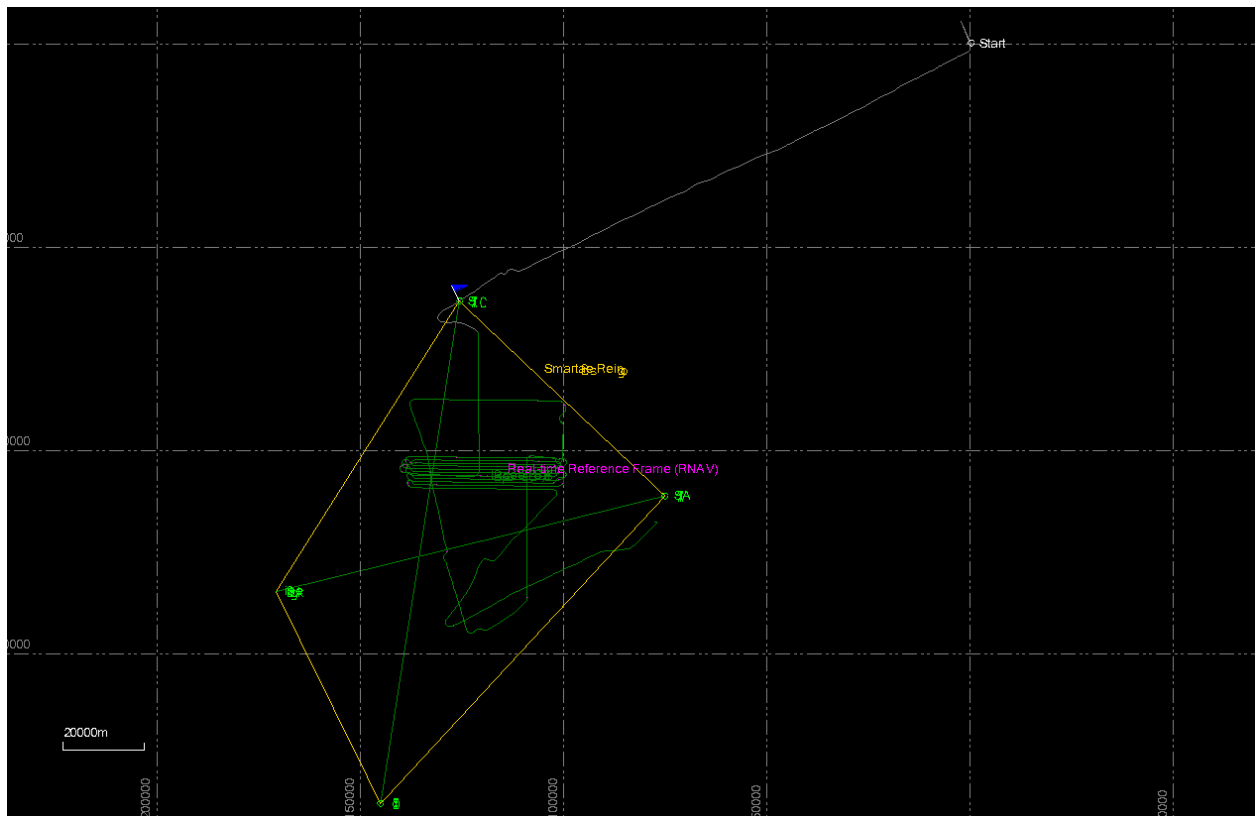
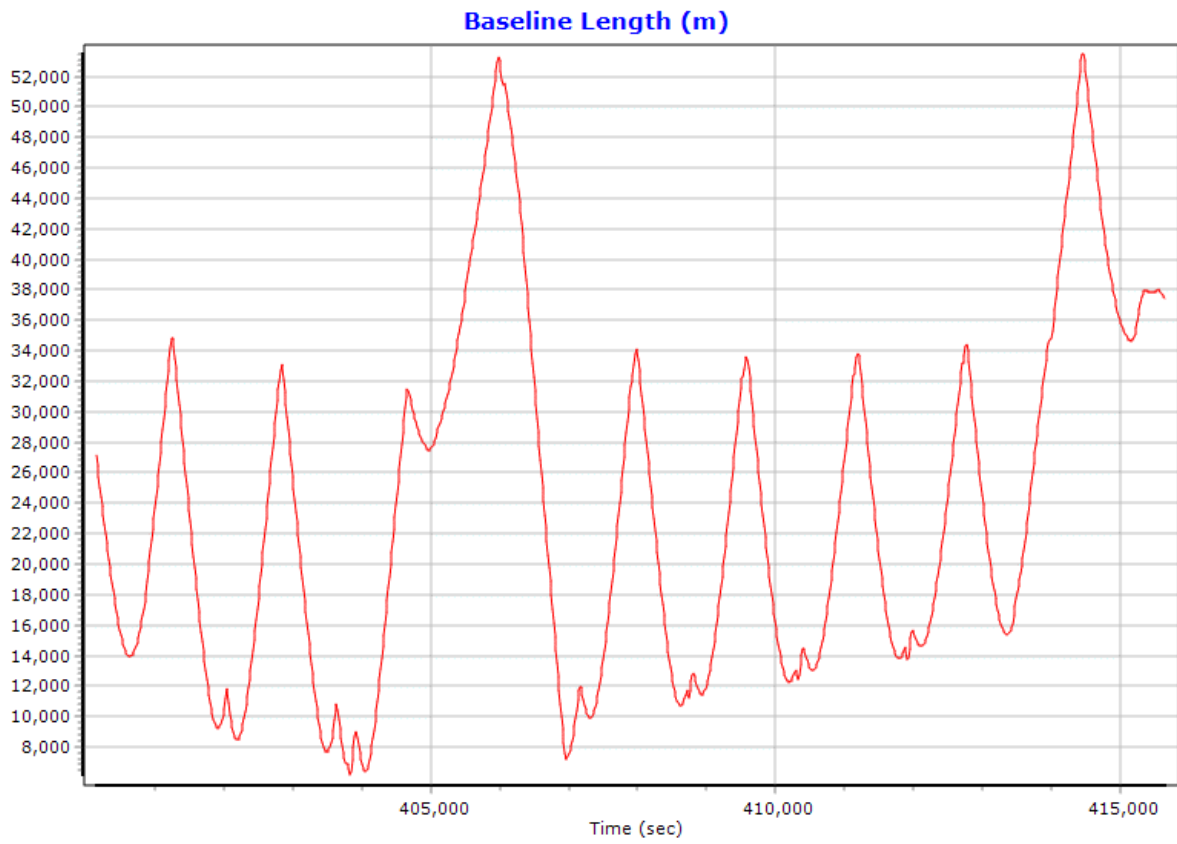
OK Cancel

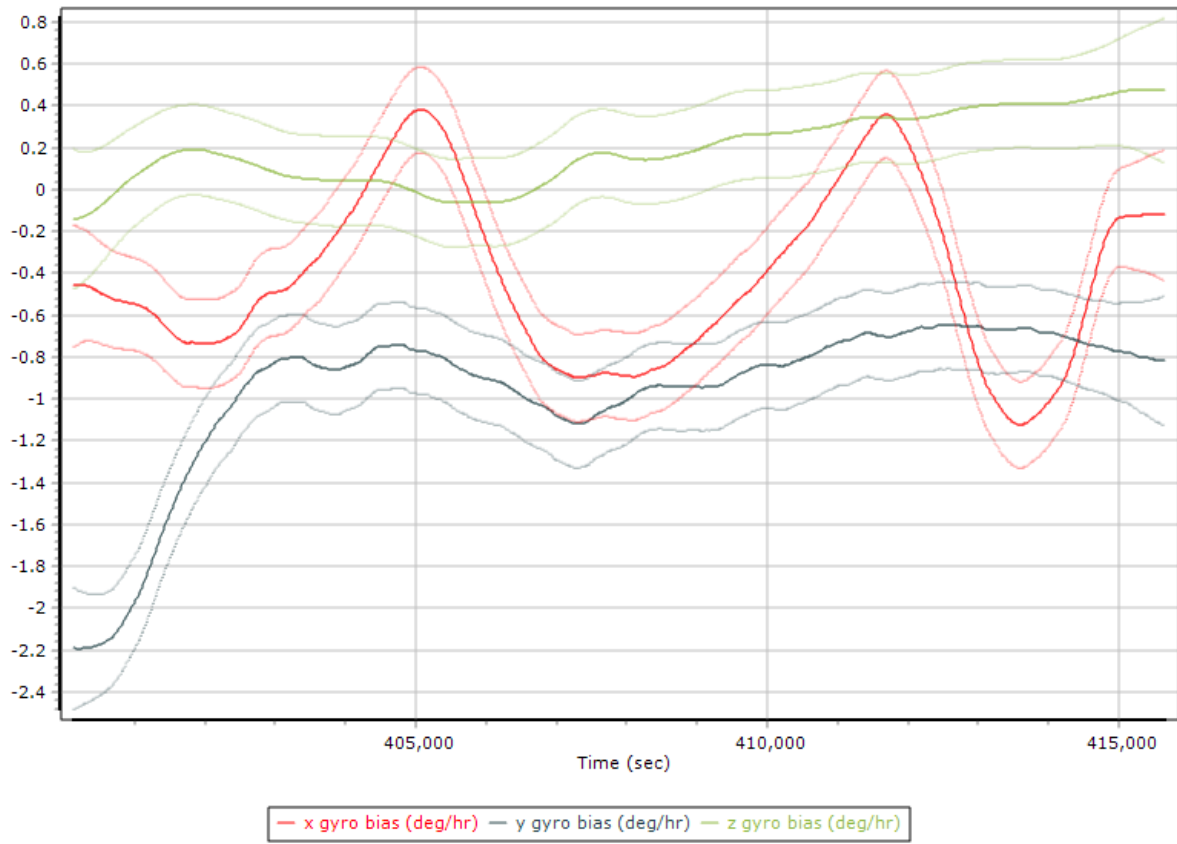
CAU18039A

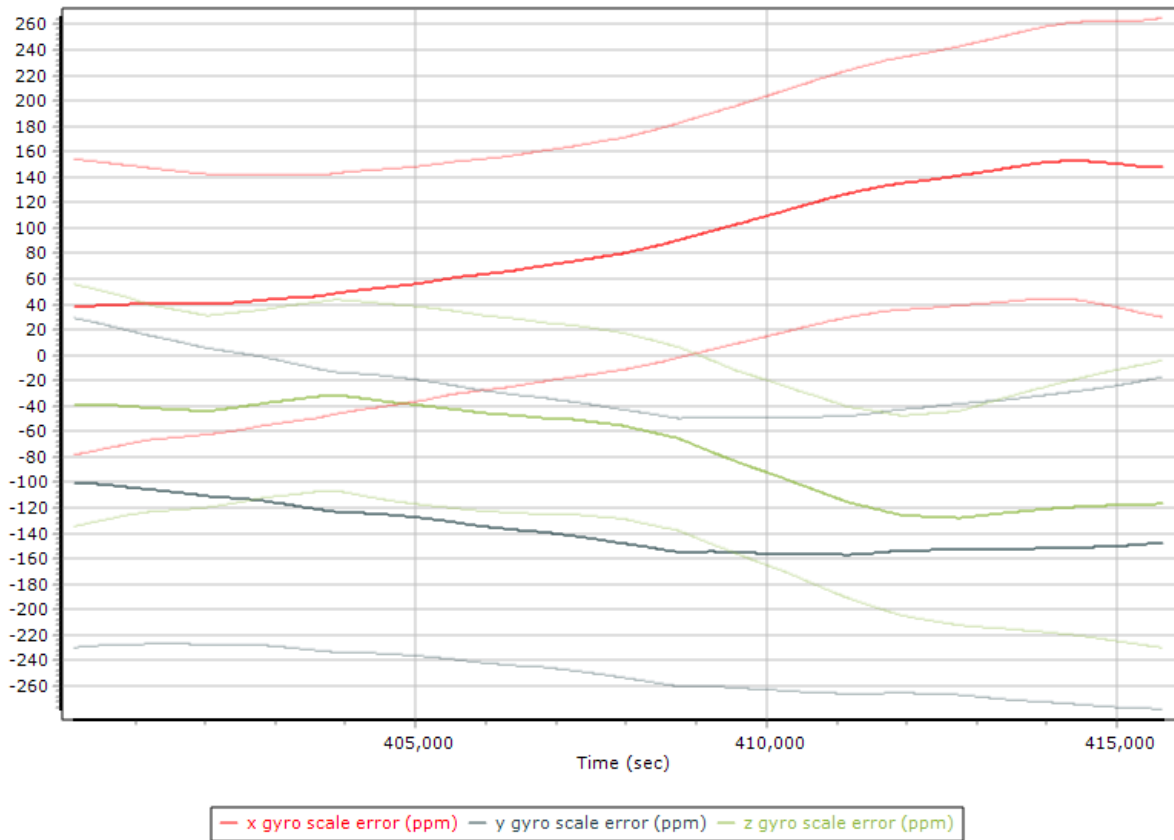












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

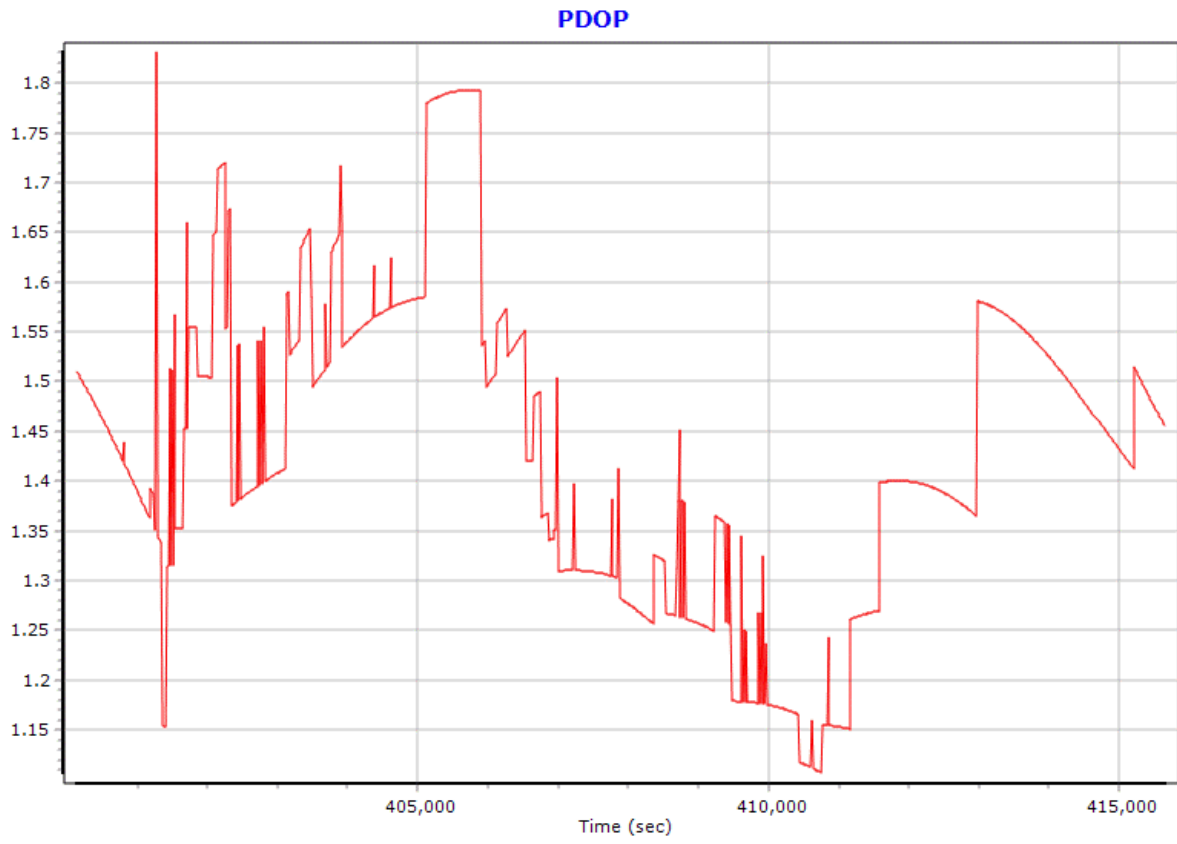
Aircraft to Reference Mounting Angles

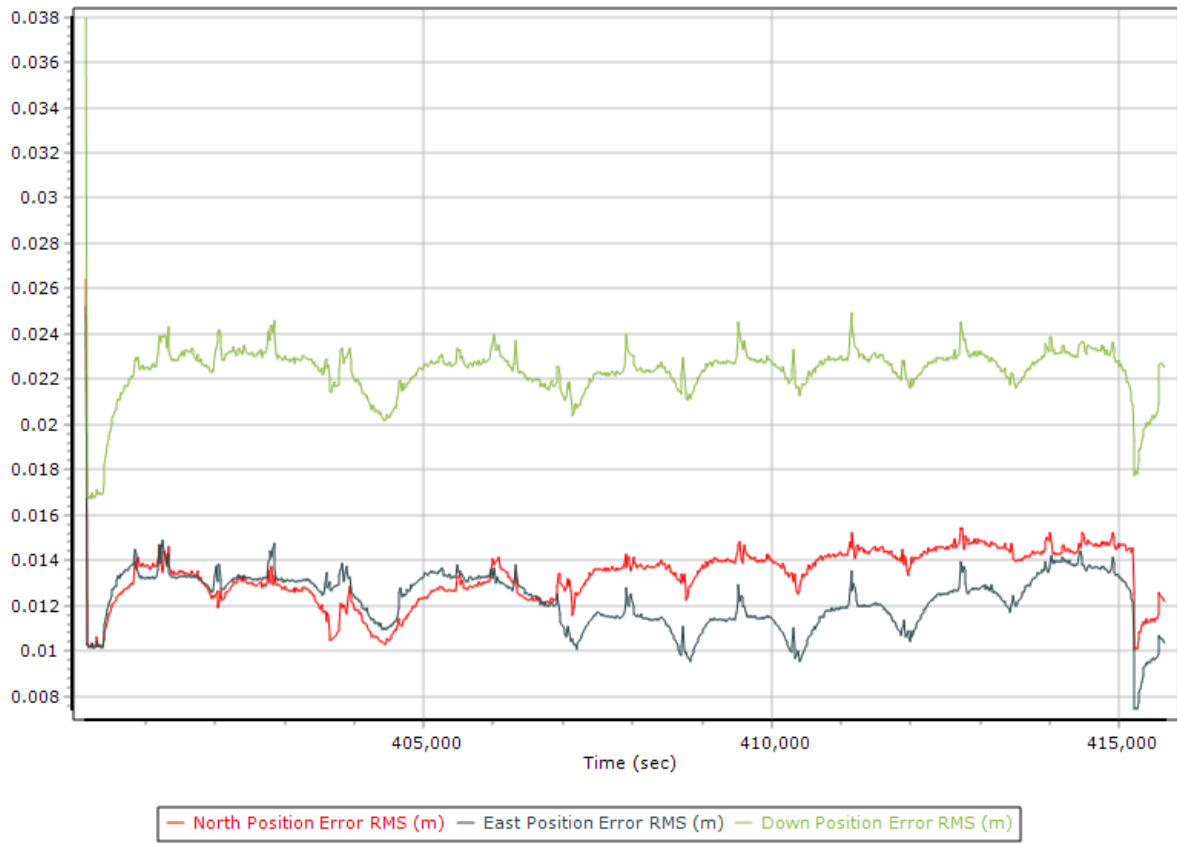
X:

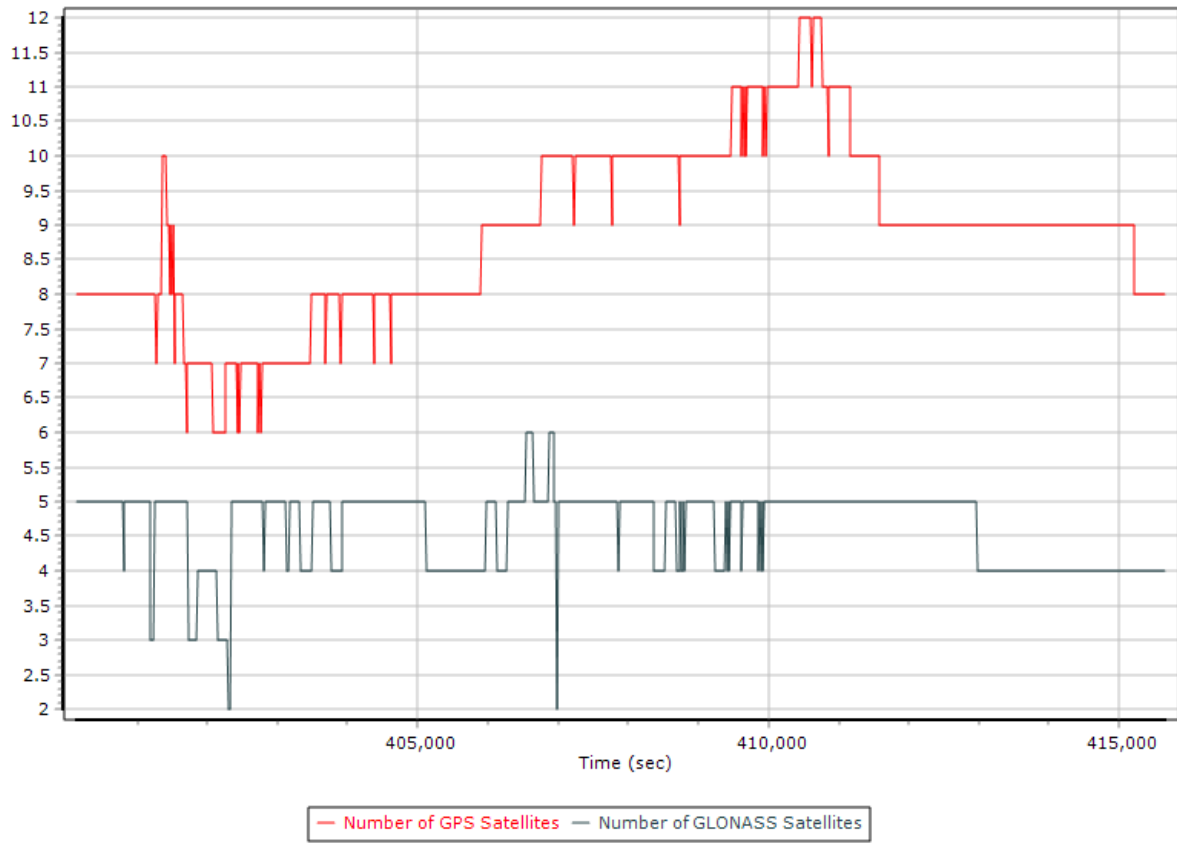
Y:

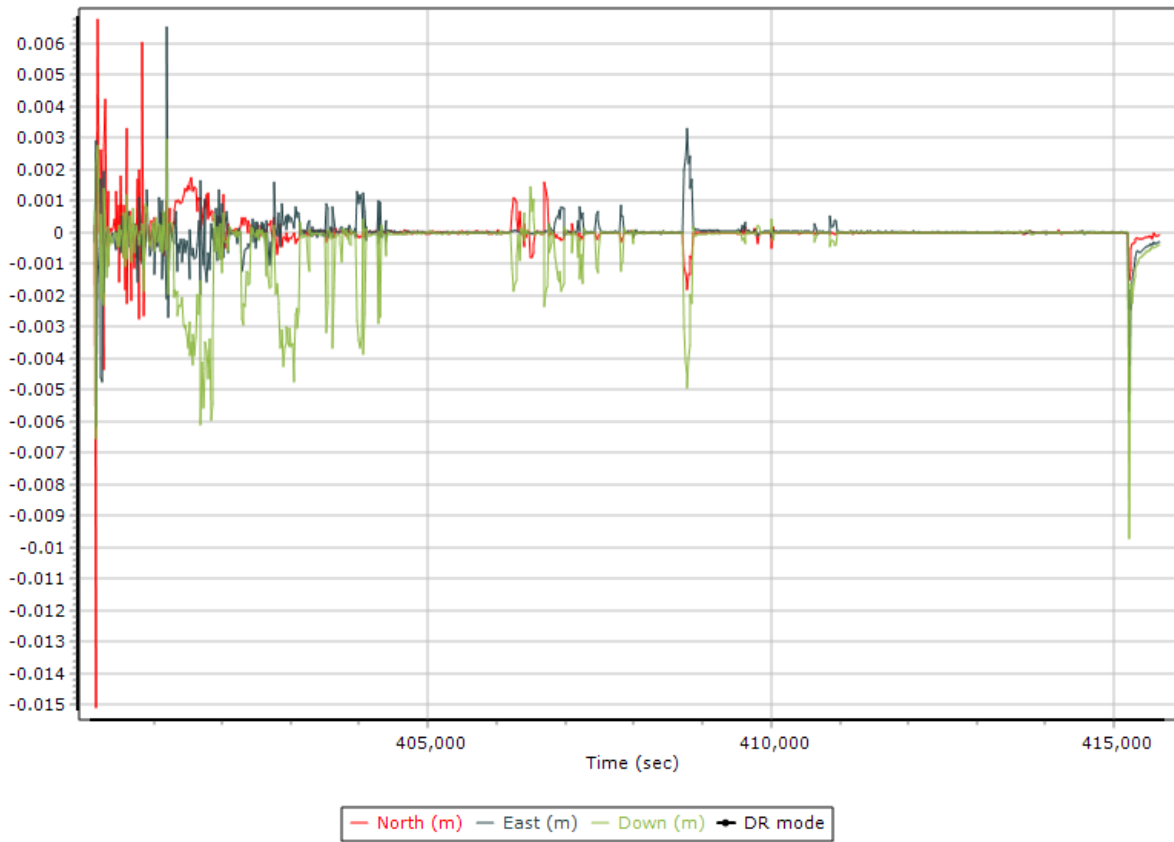
Z:

OK Cancel









Project Settings ✕

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

Timing

Start: Data Incr. (sec)

End: Output Record 0.005000

Entire time interval IMU 0.005000

Seconds of start week Primary GNSS 1.000000

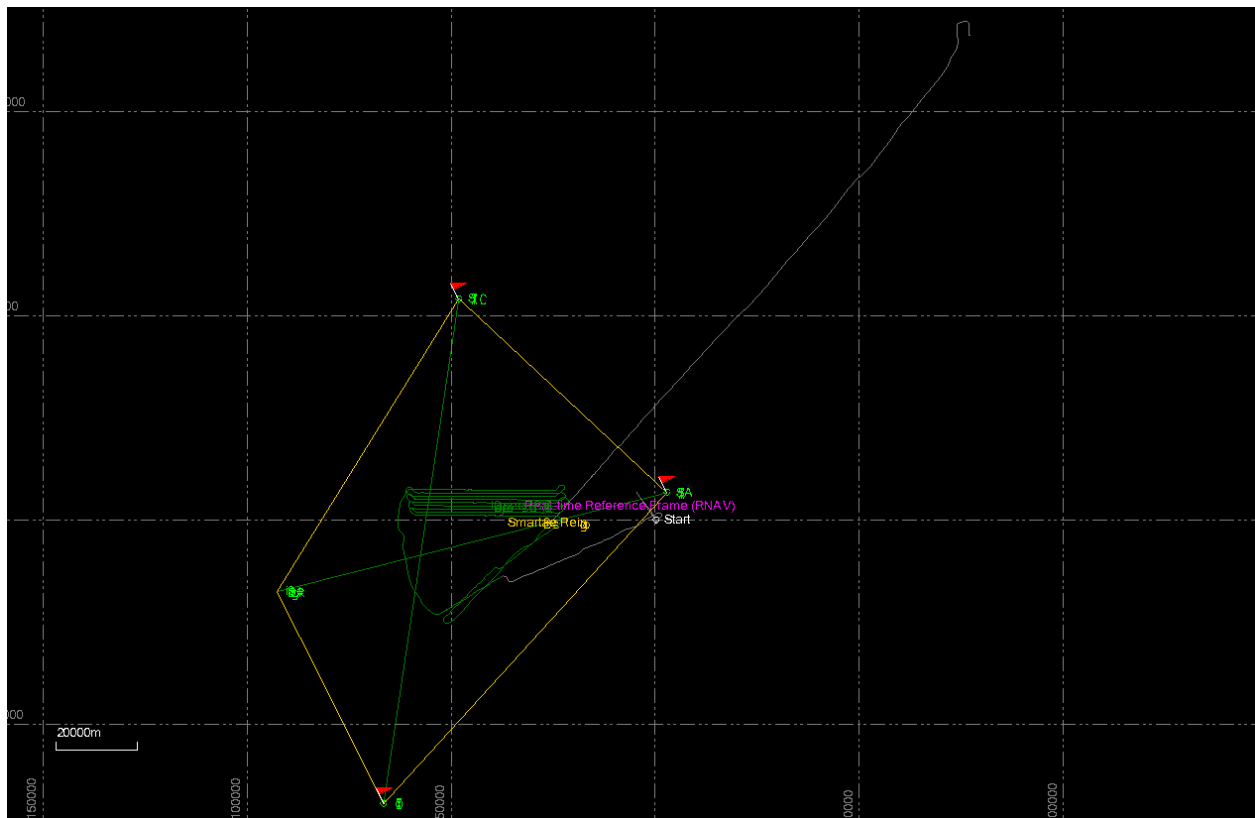
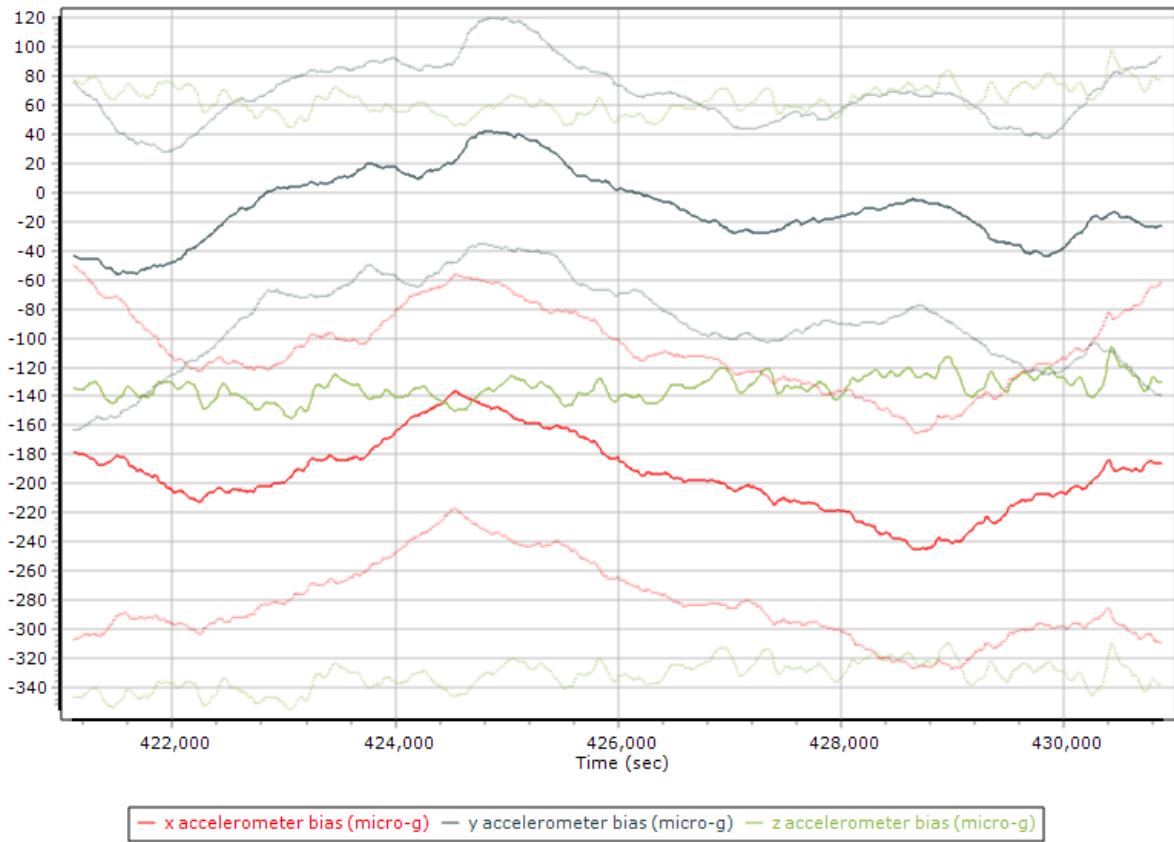
UTC Offset:

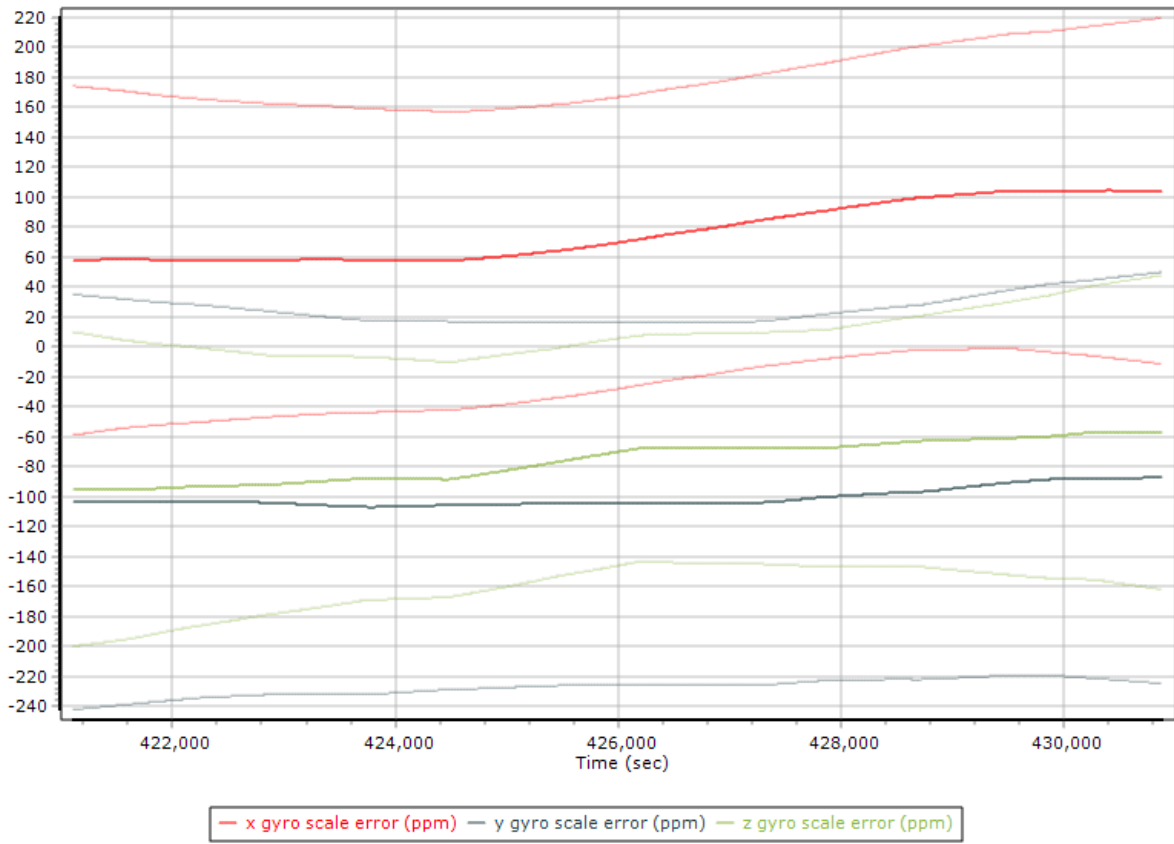
Processable Time Windows

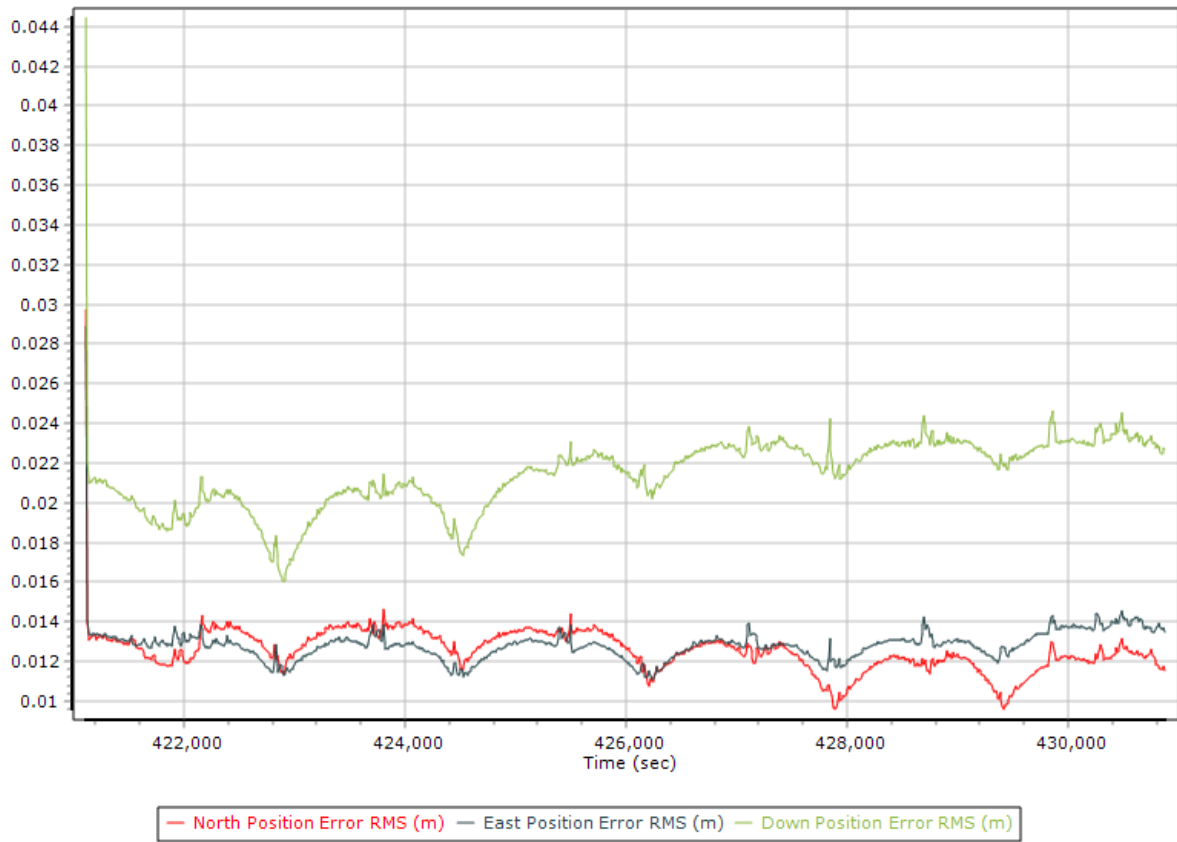
Start after launch Wait Time: sec

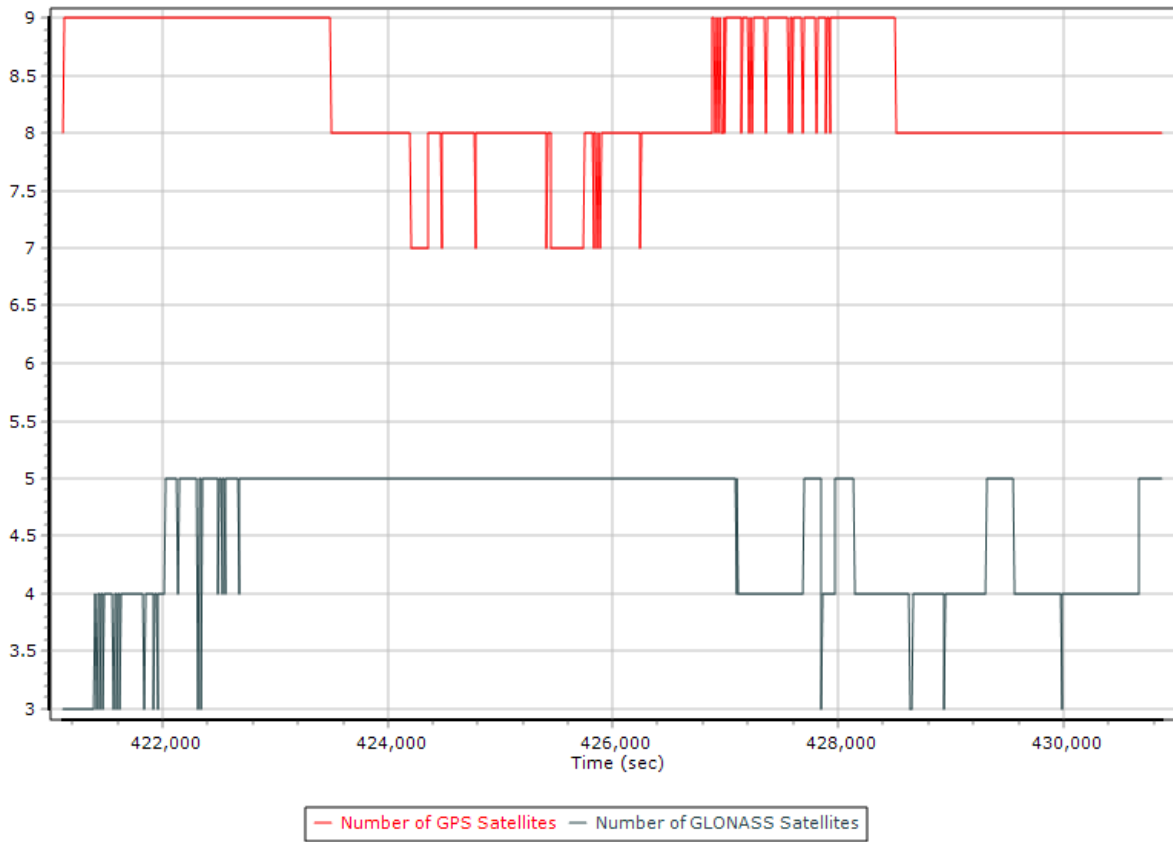
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	396383.000	415681.000	19298.000	End of file

CAU18039B









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: 419653.000
End: 433777.000

Entire time interval
 Seconds of start week

UTC Offset: 18.000

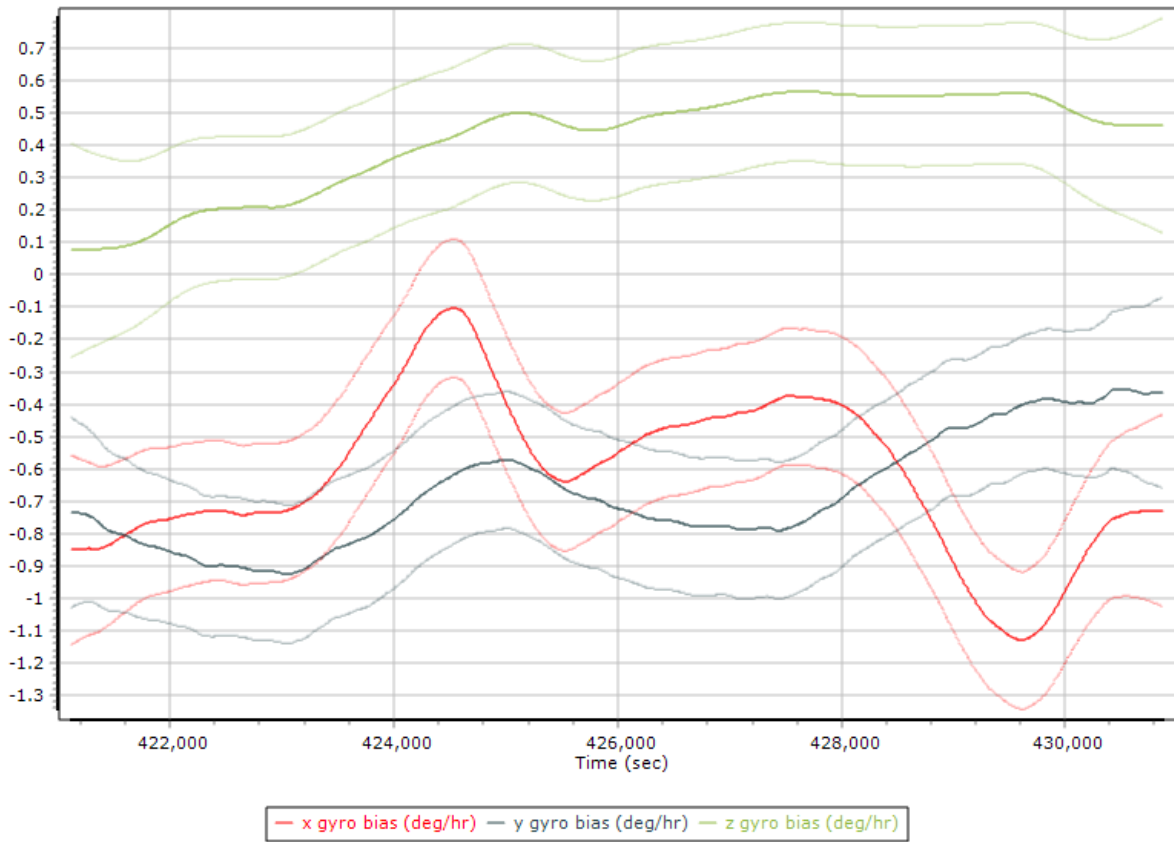
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

Processable Time Windows

Start after launch Wait Time: 4.000 sec

	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	419653.000	433777.000	14124.000	End of file

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

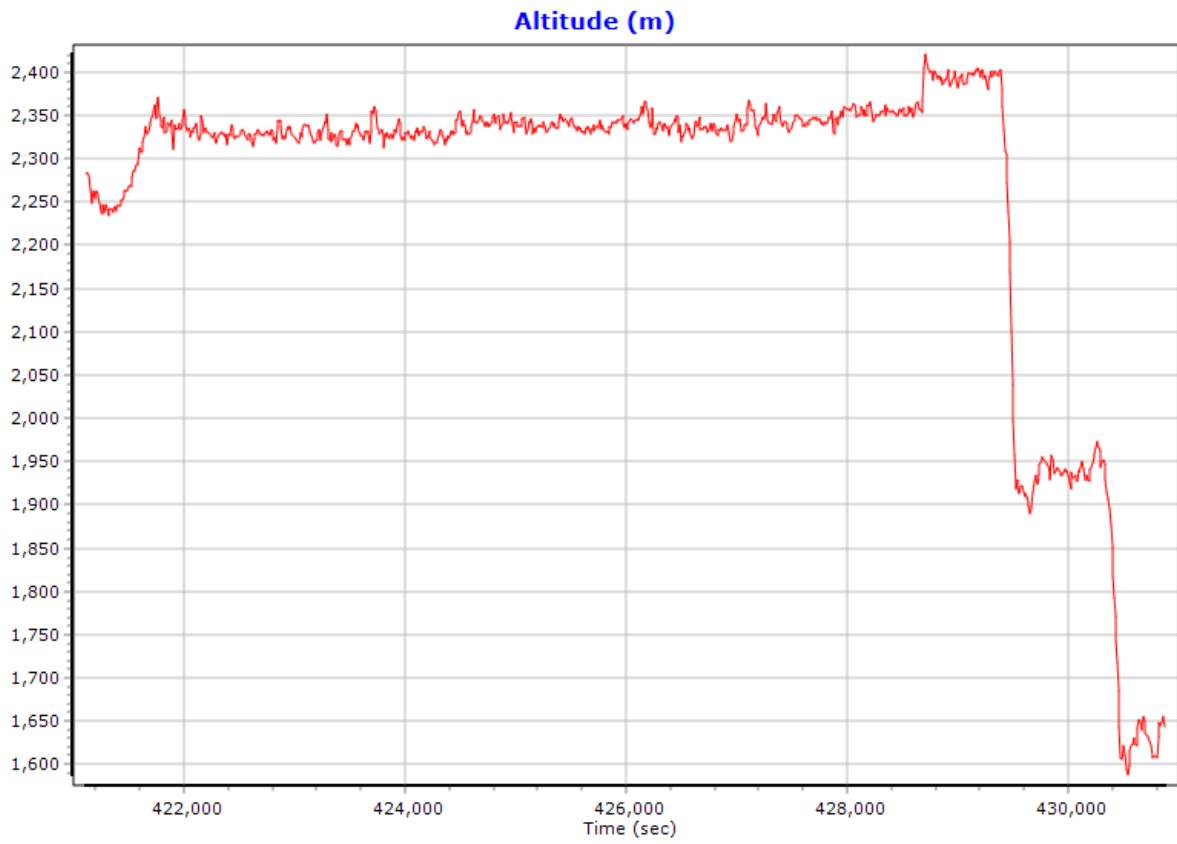
Standard Deviation: <3cm 10cm 50cm 1m 10m

Aircraft to Reference Mounting Angles

X:

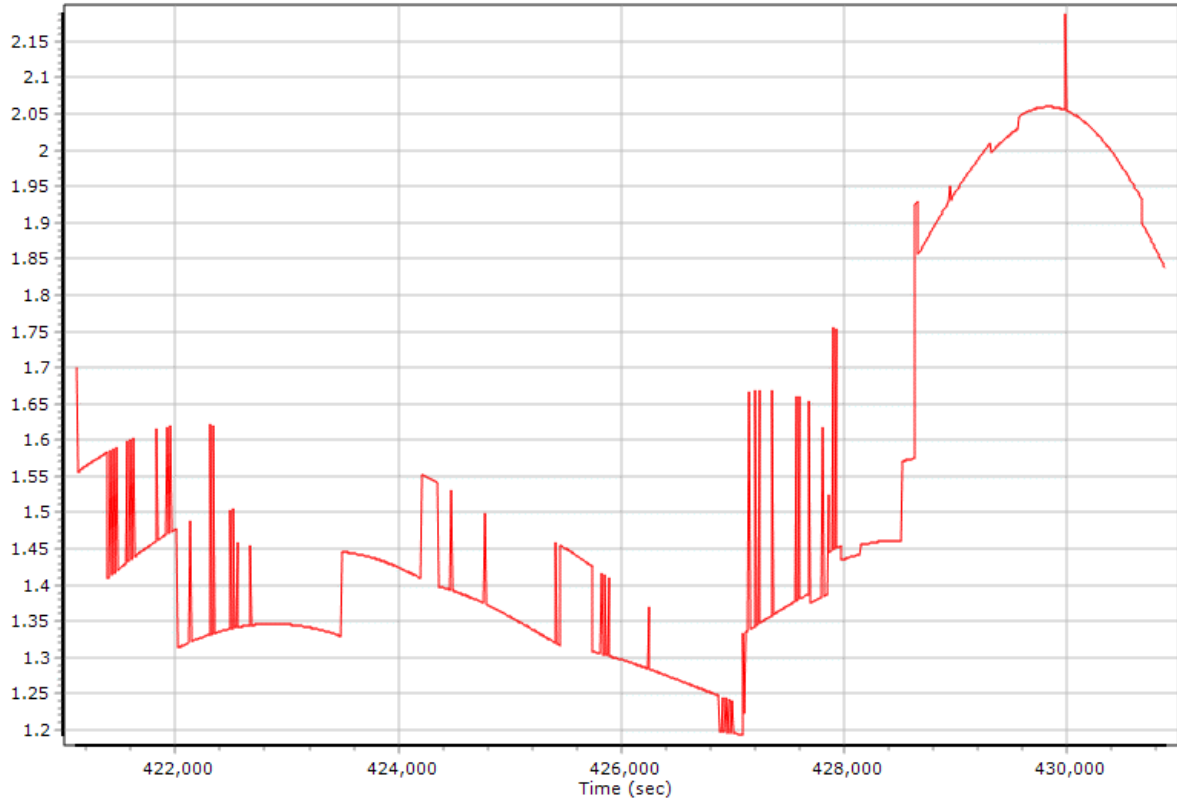
Y:

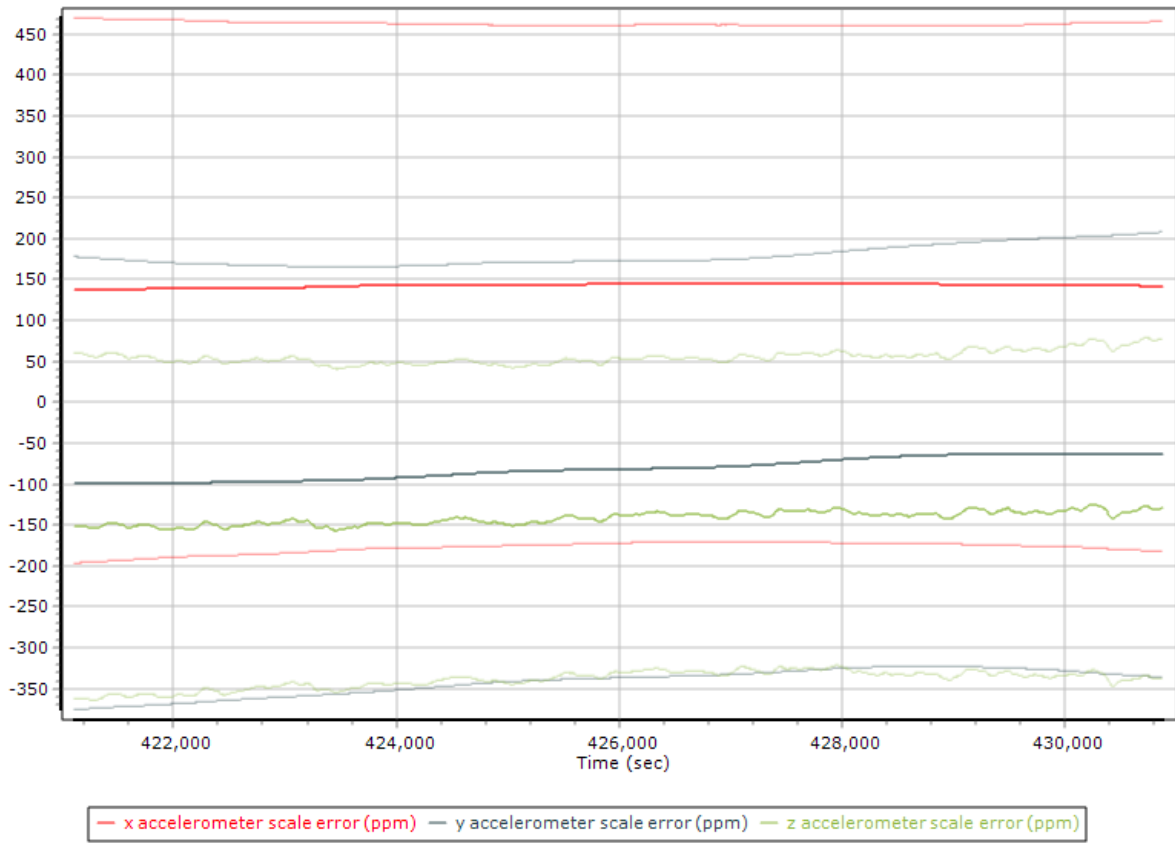
Z:

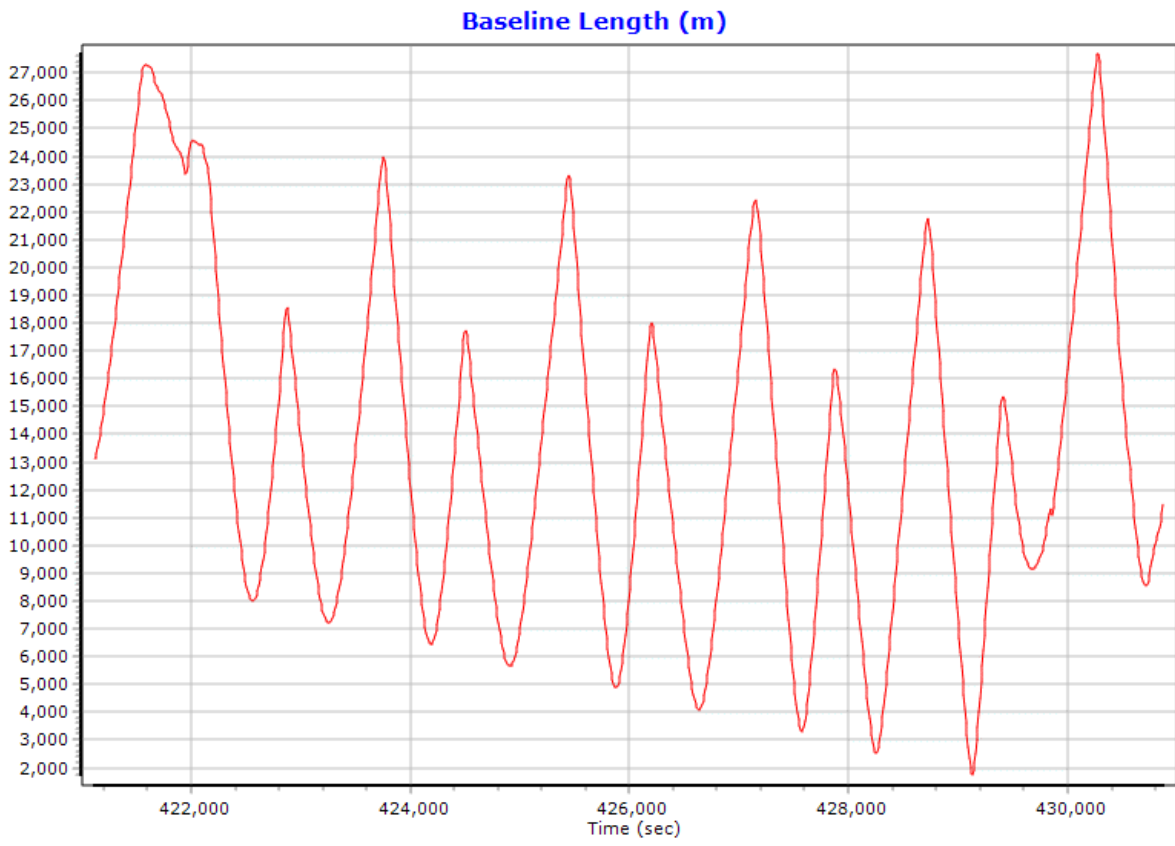




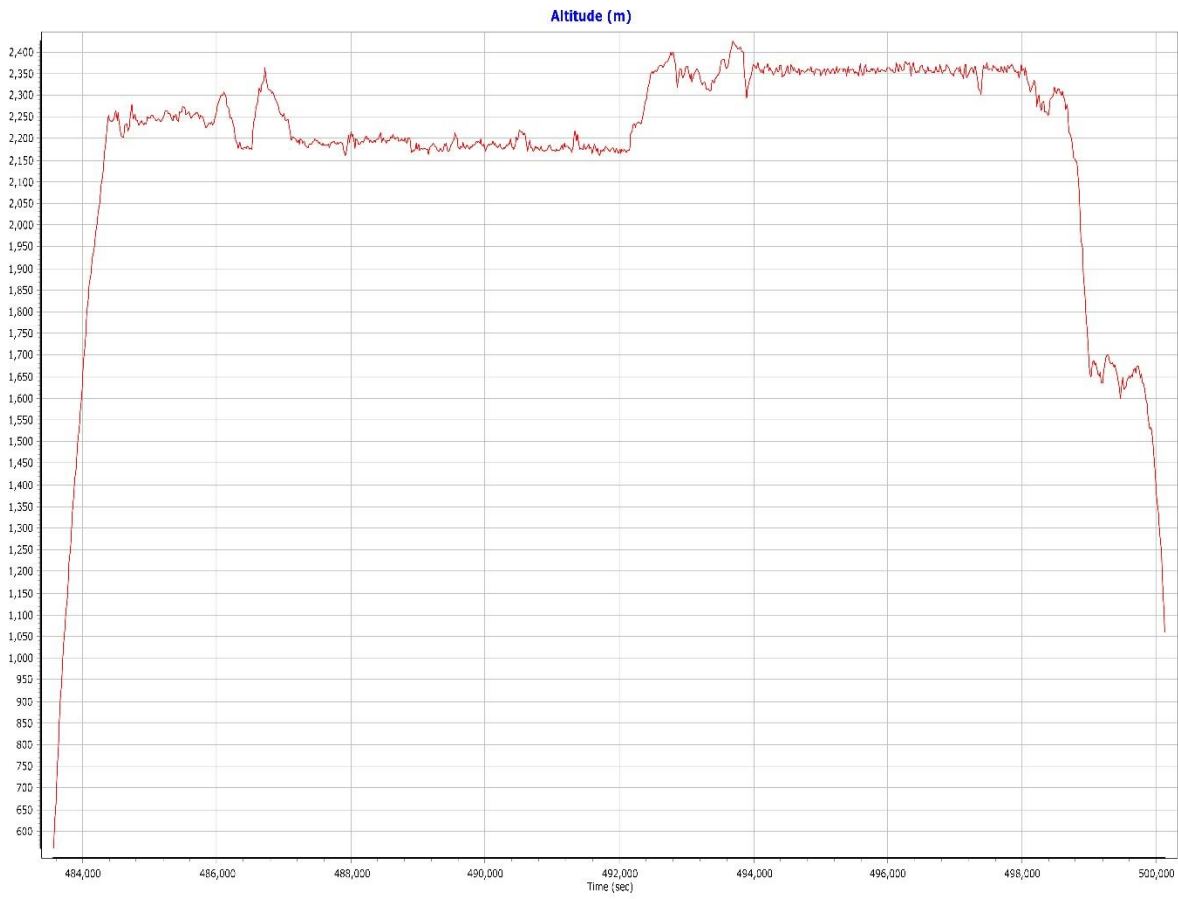
PDOP

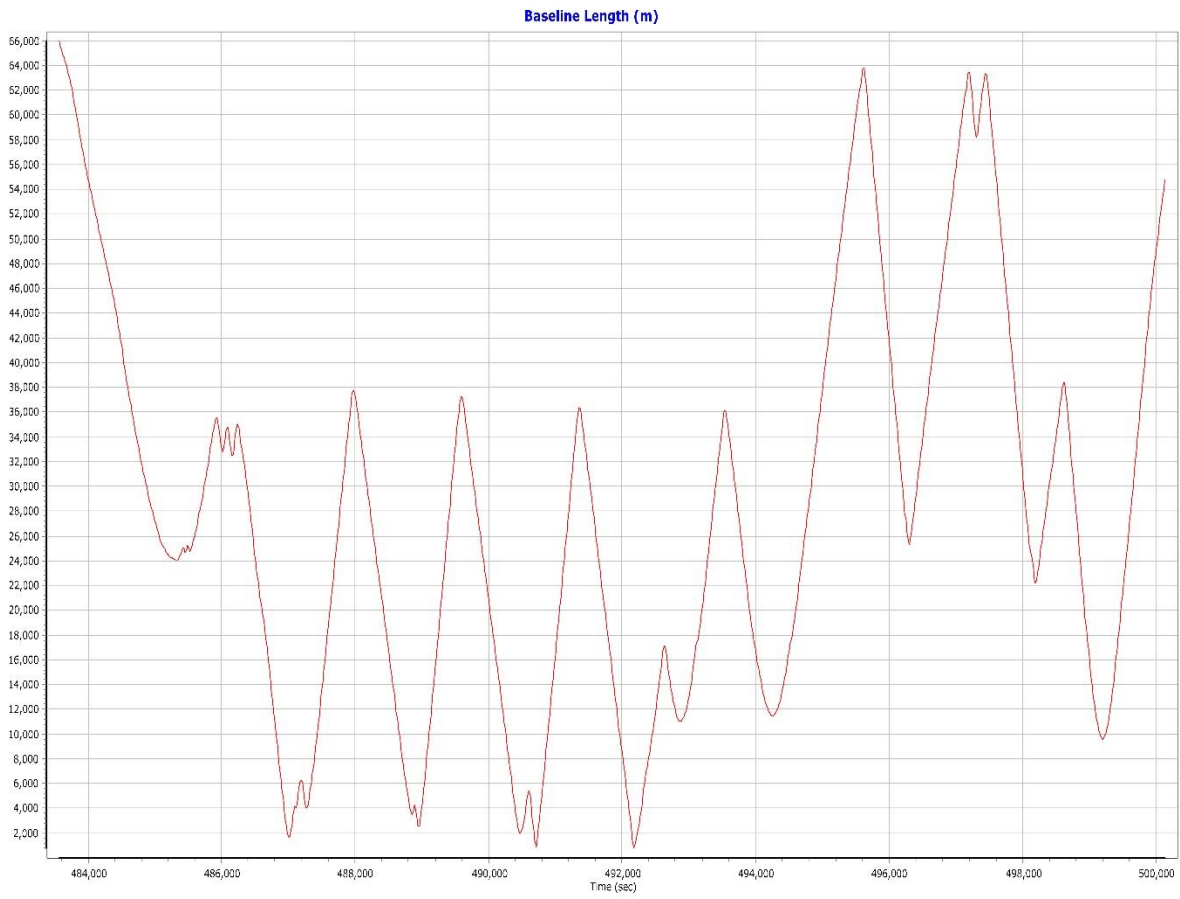


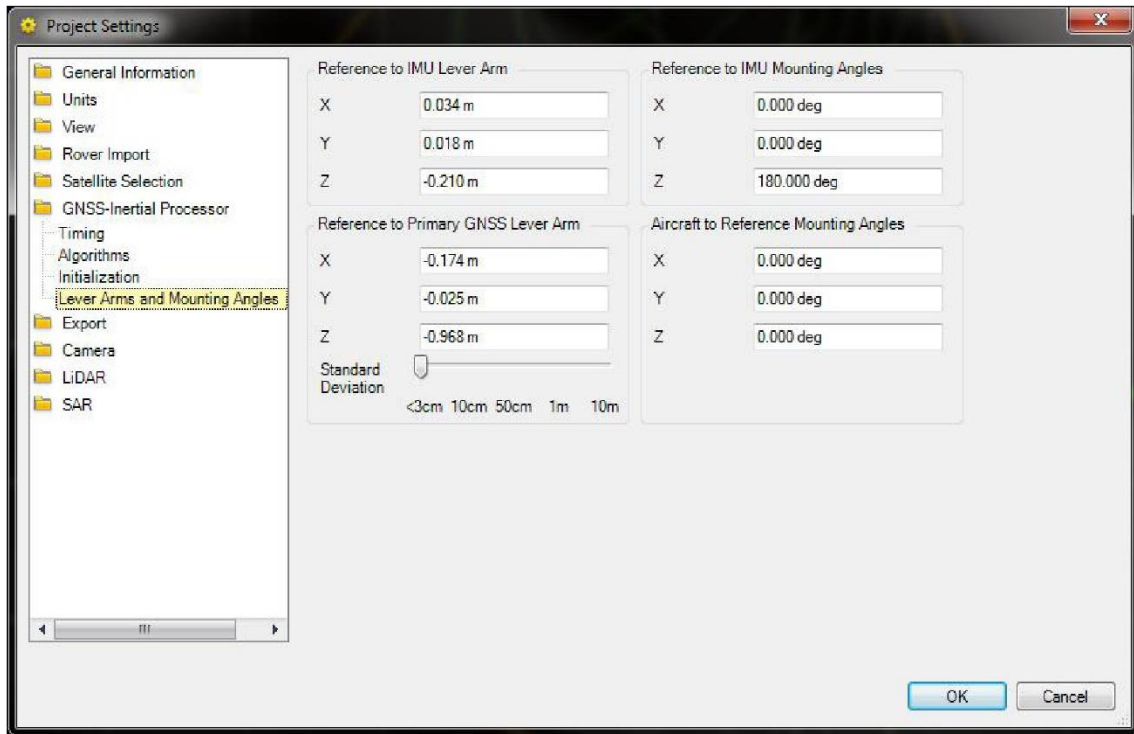


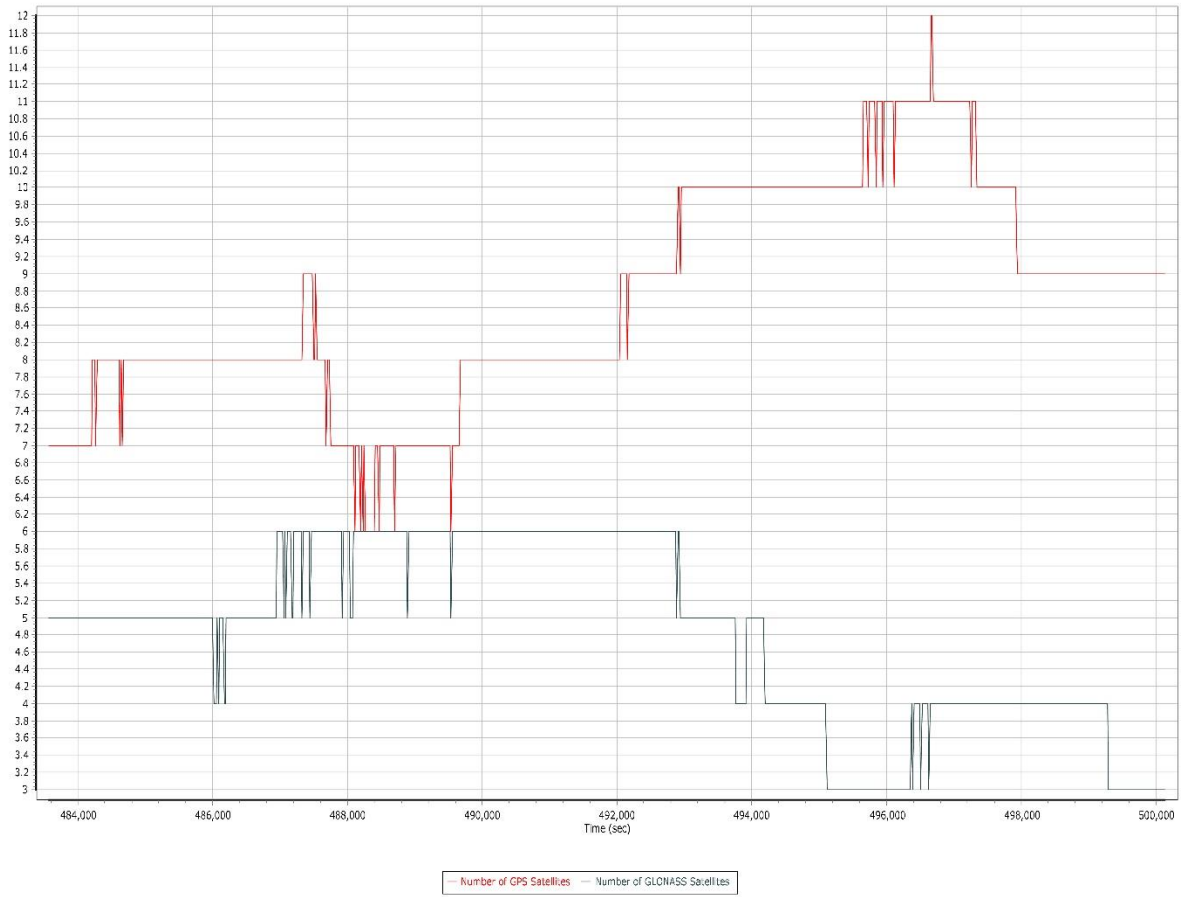


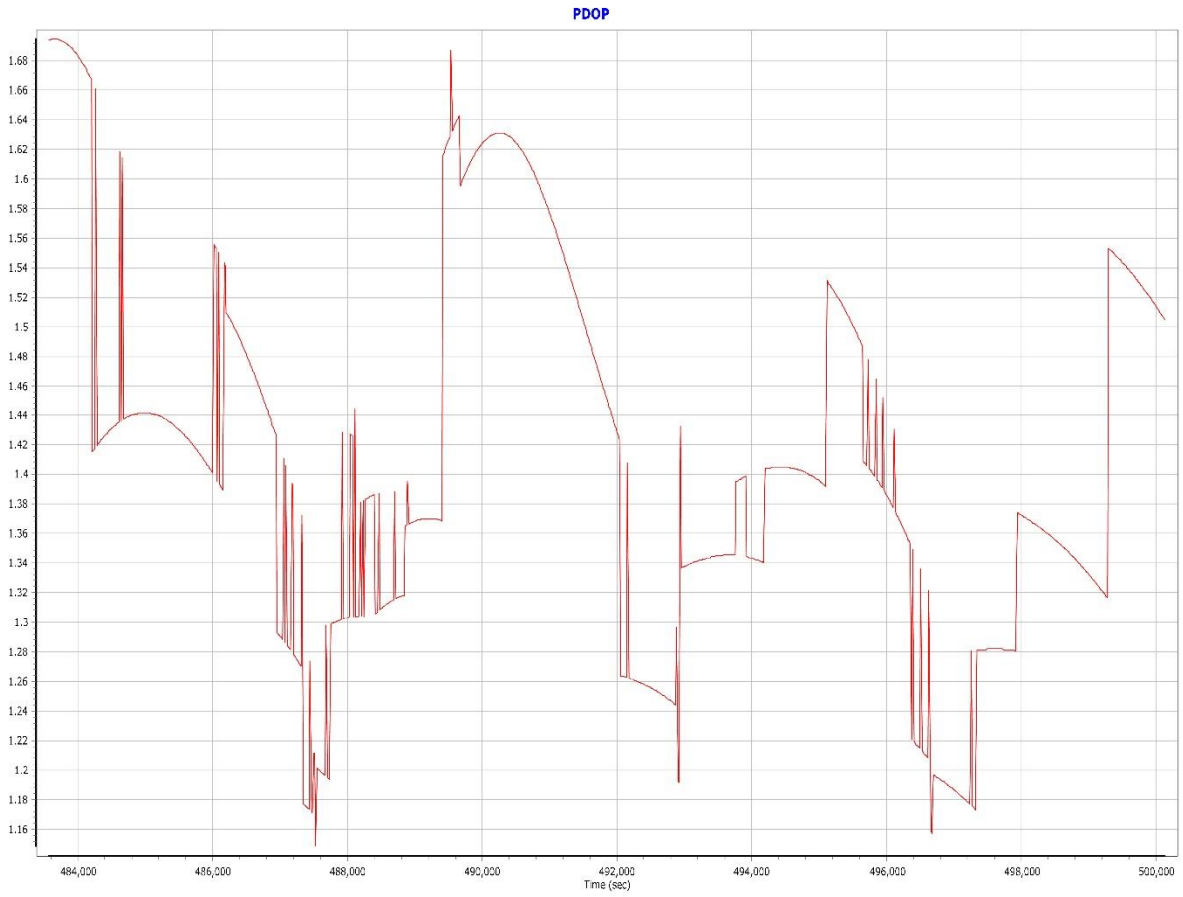
CAU18040A

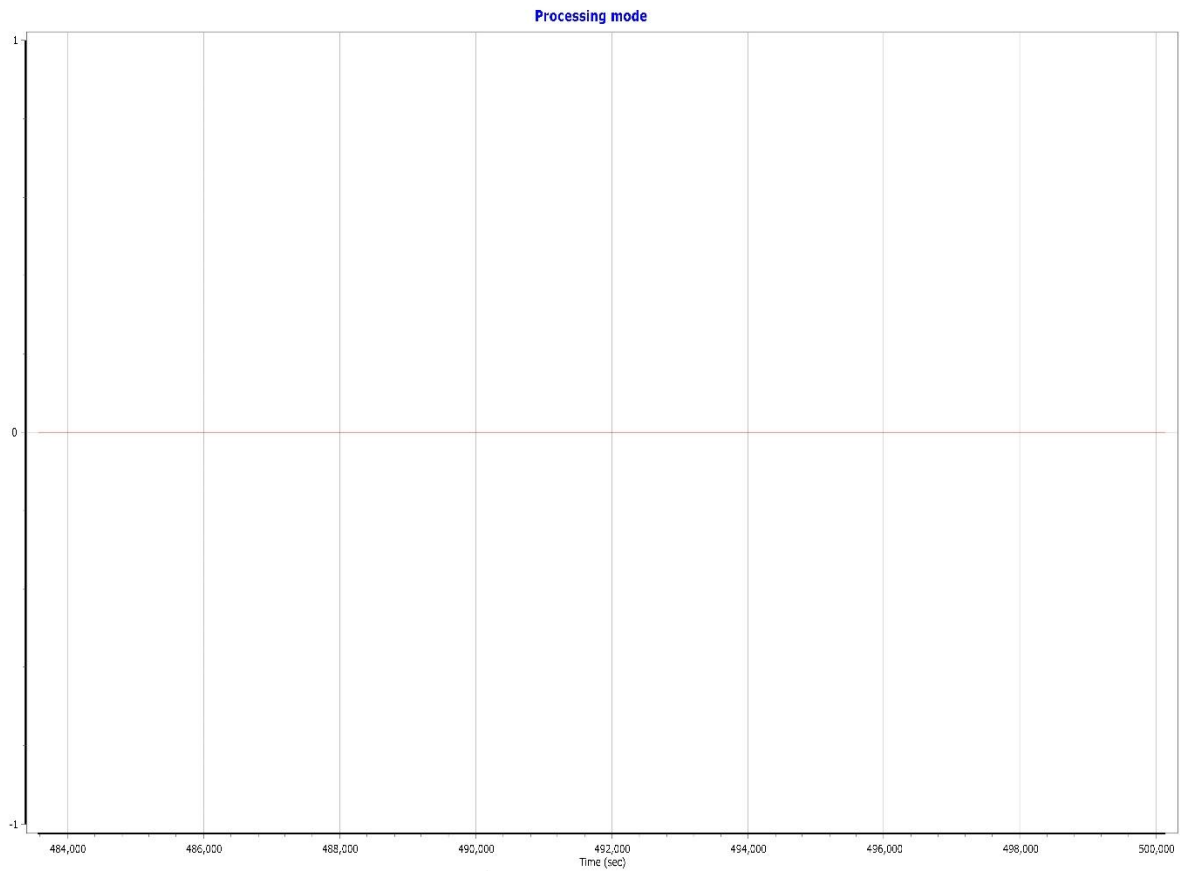






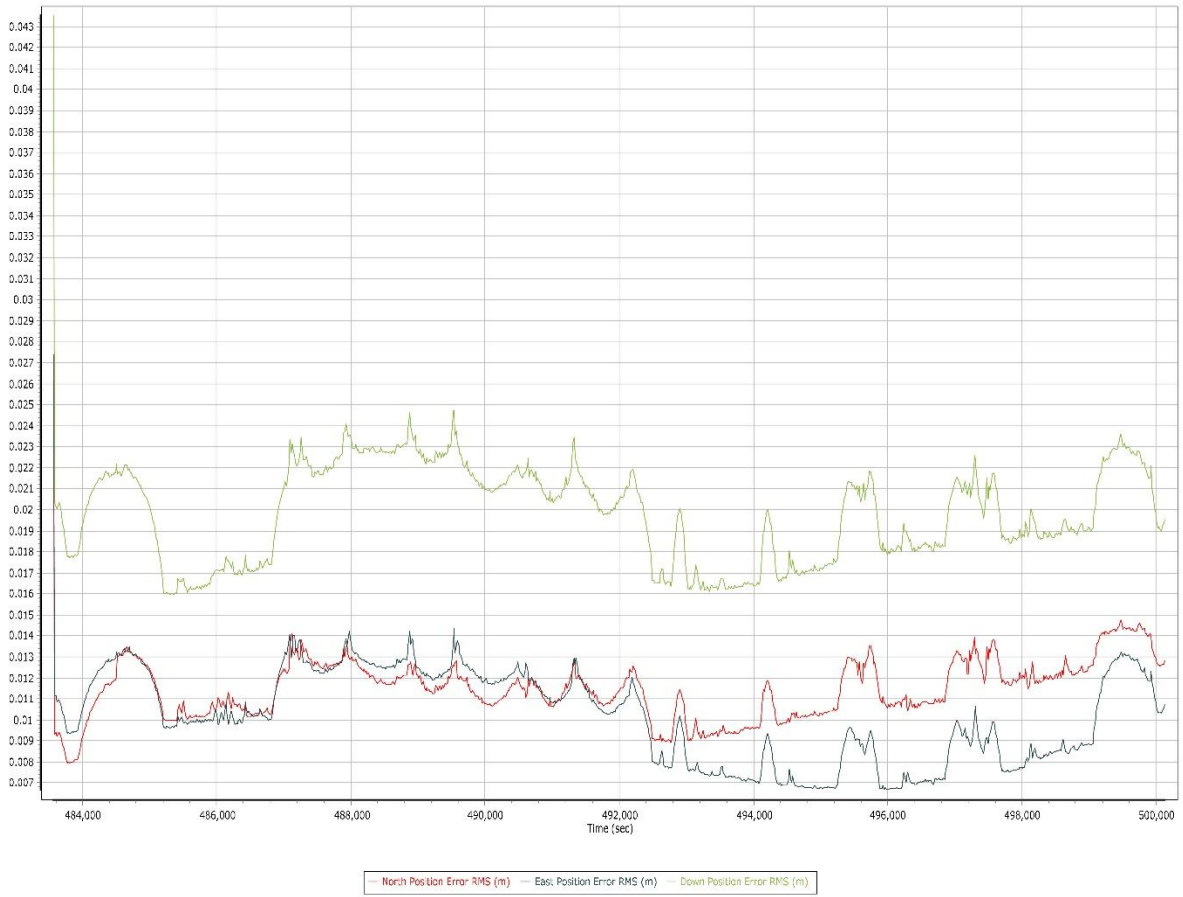


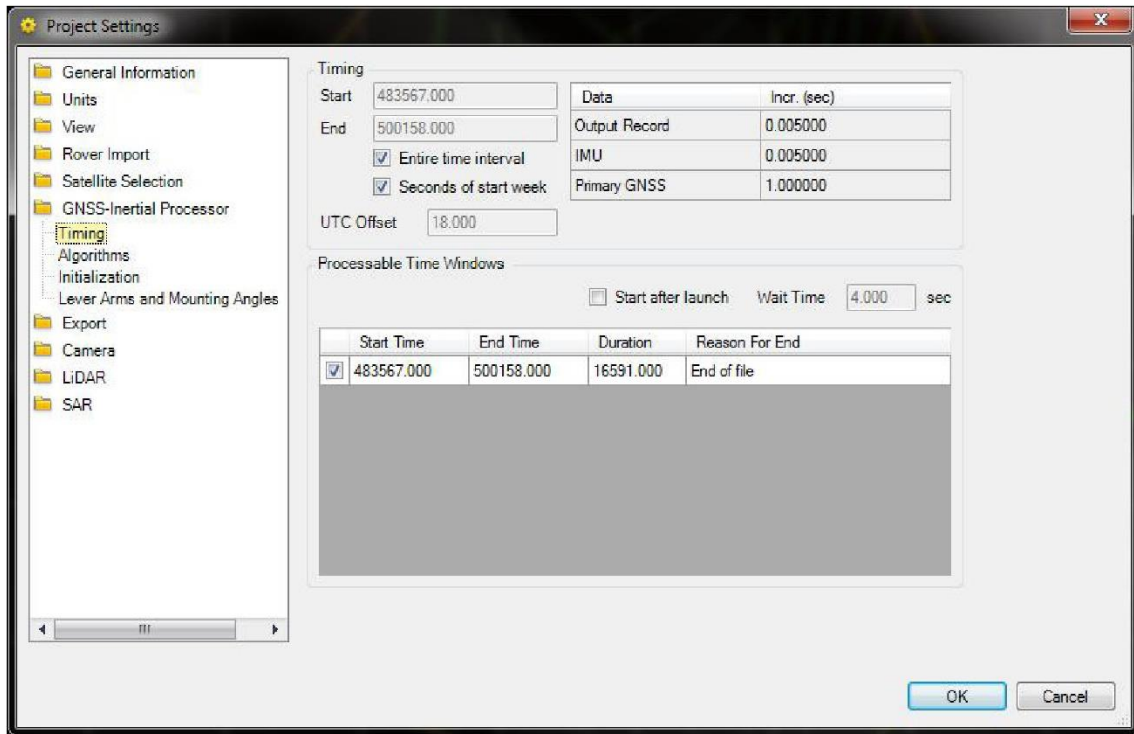


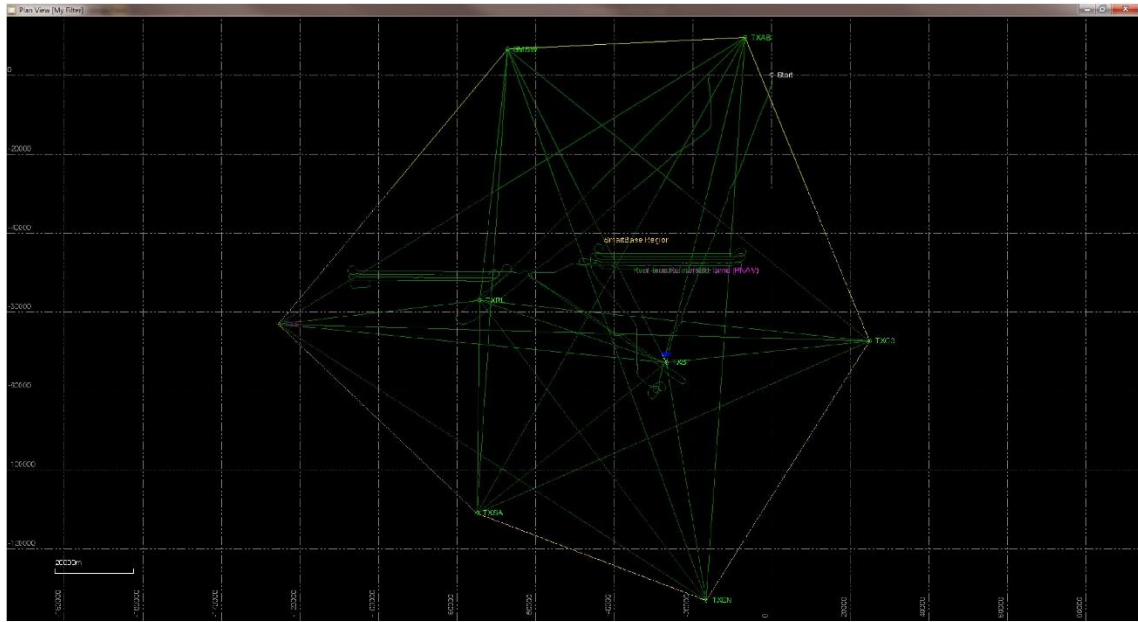


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IA*PPF, 6 = C/A, 7 = GNSS Nav, 8 = DR

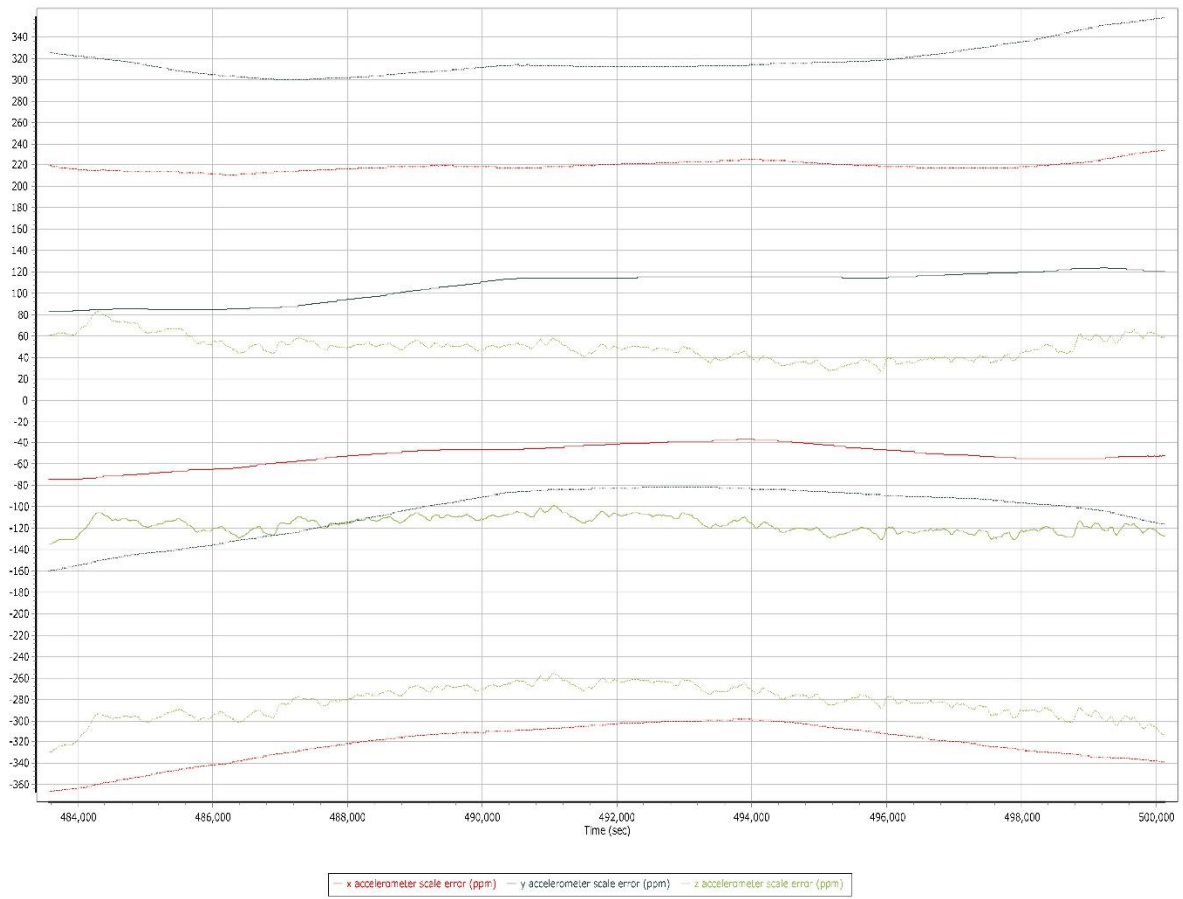


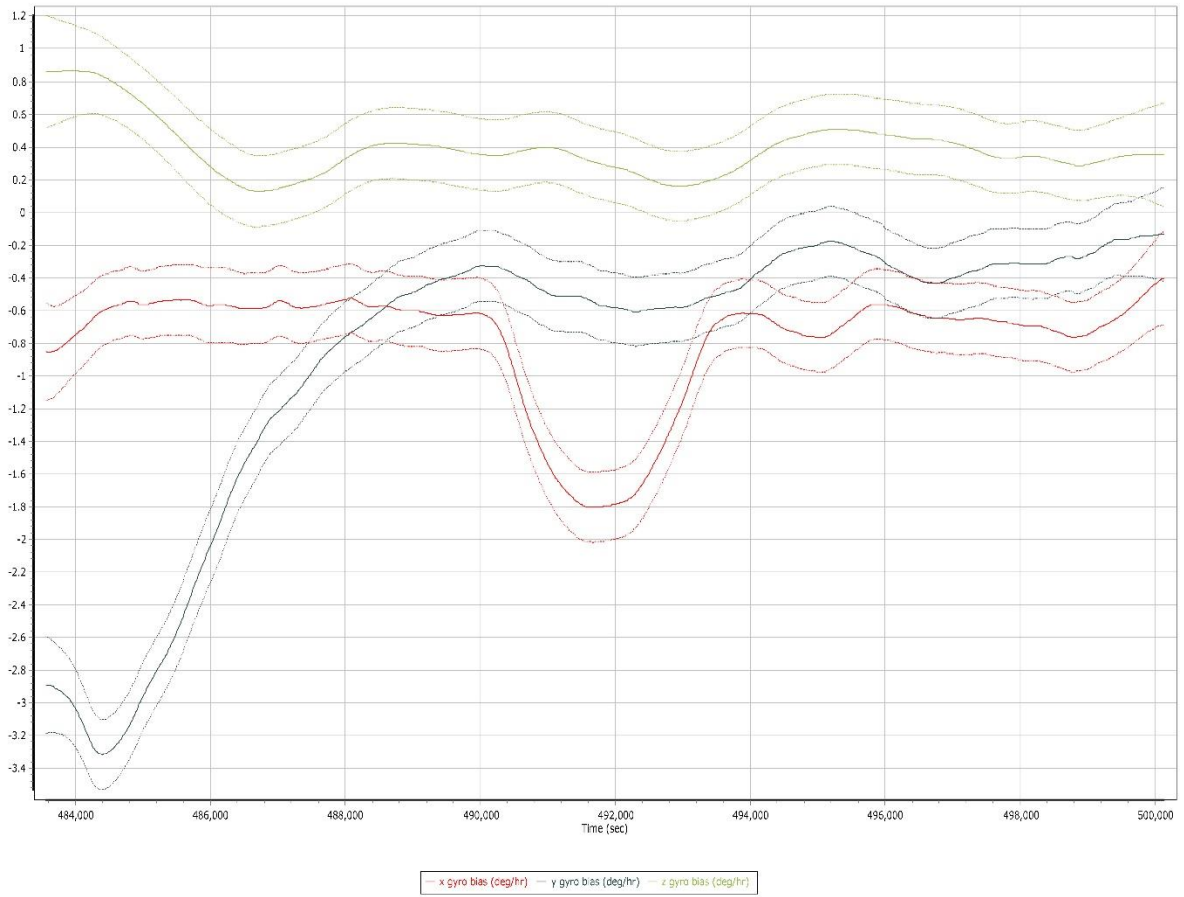


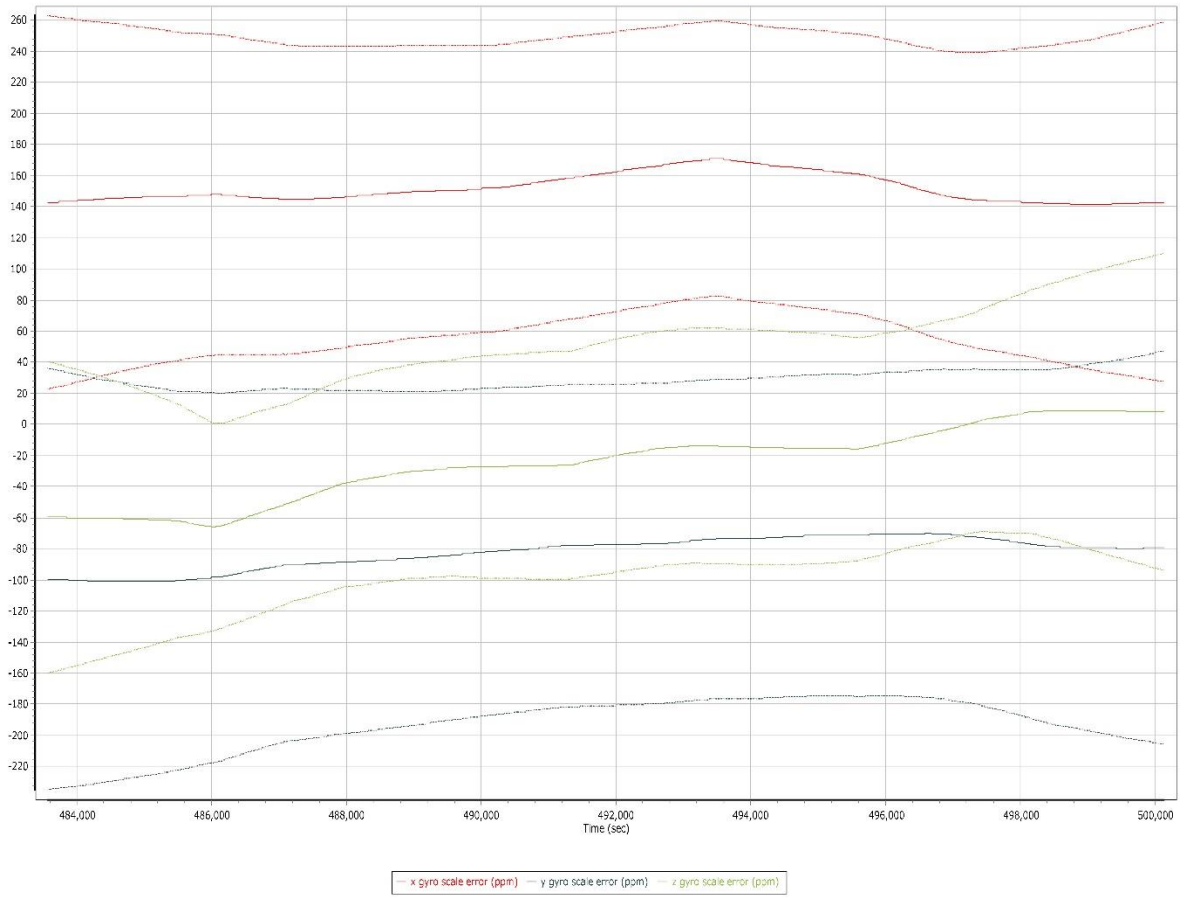




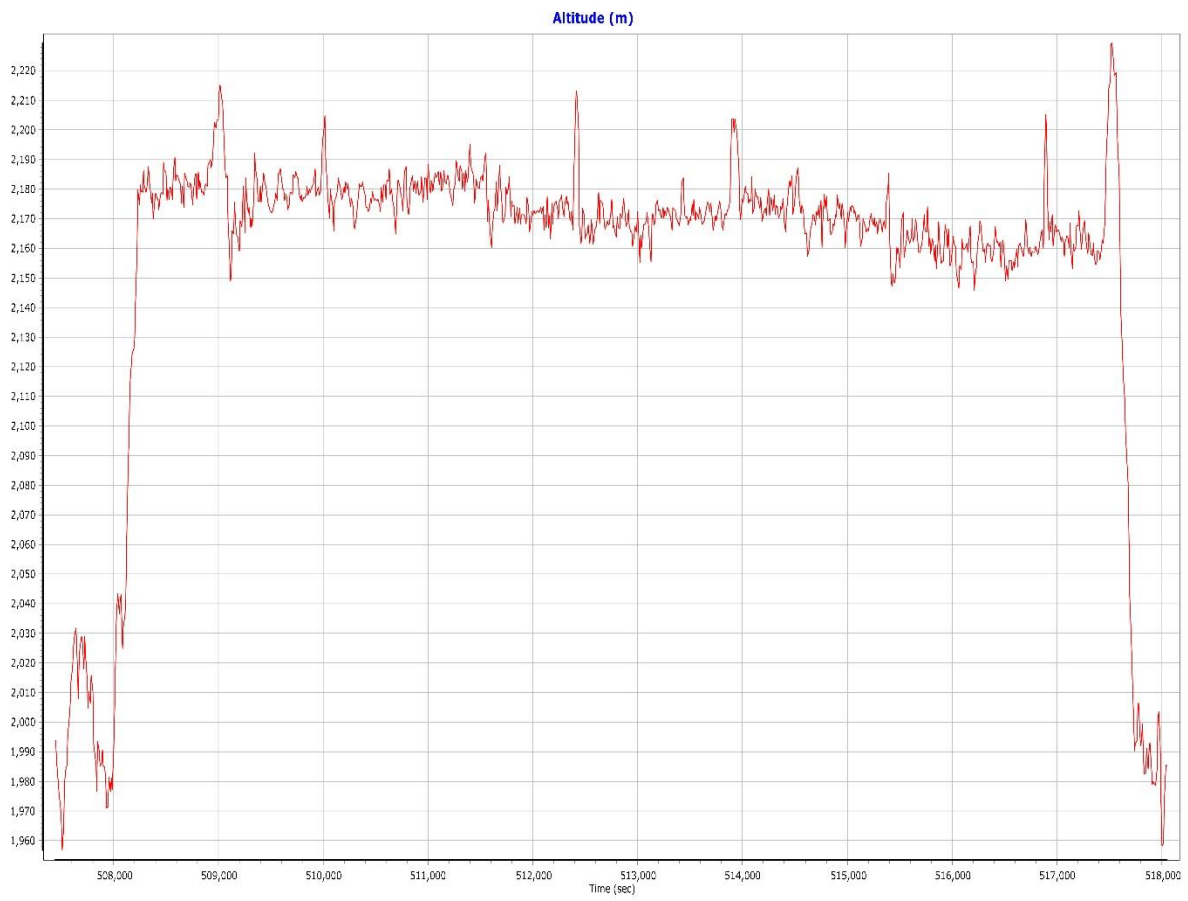


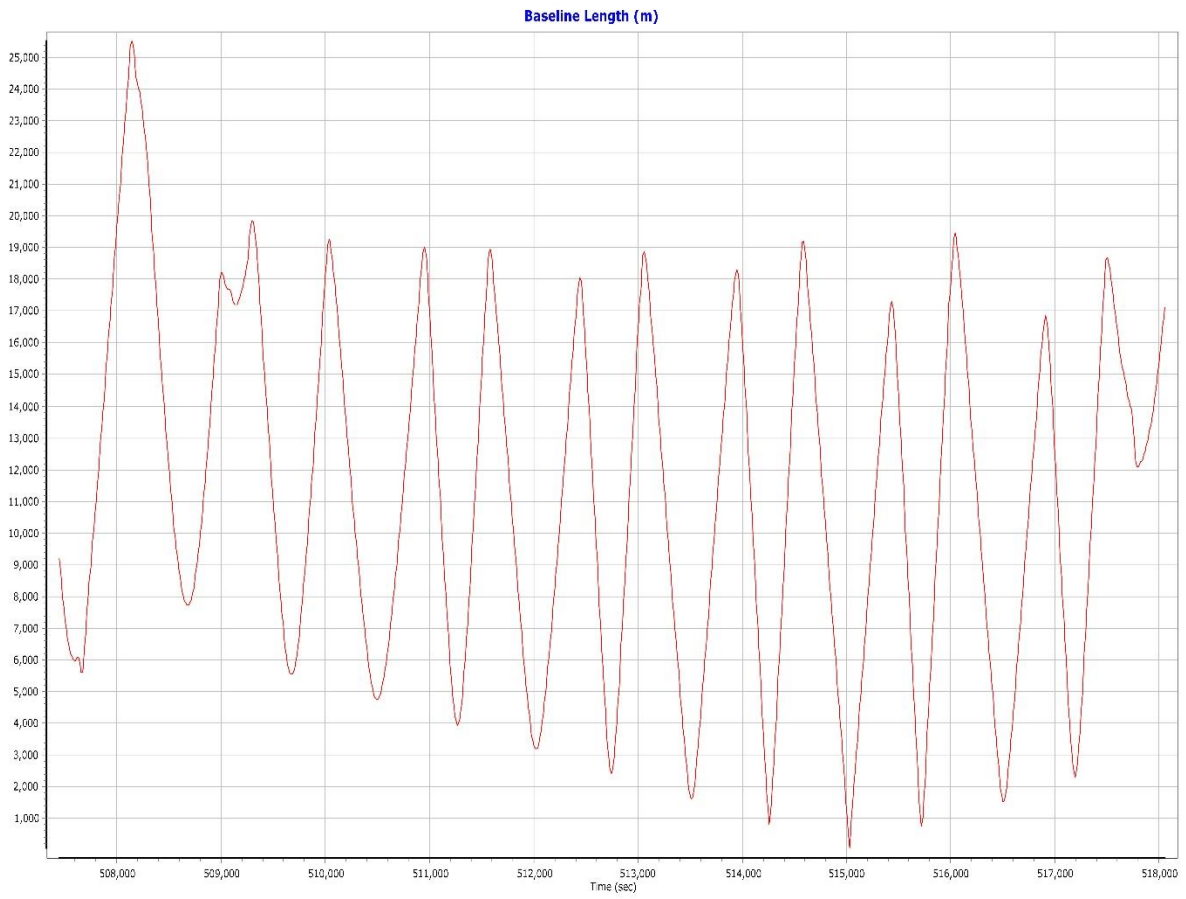


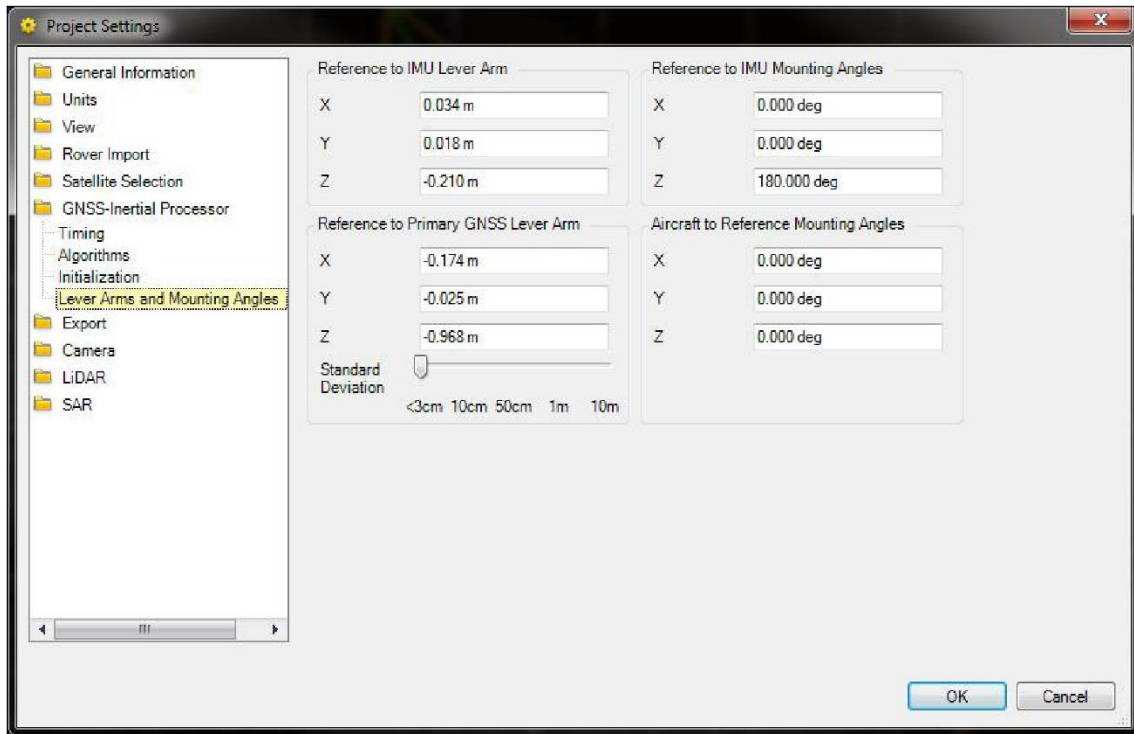


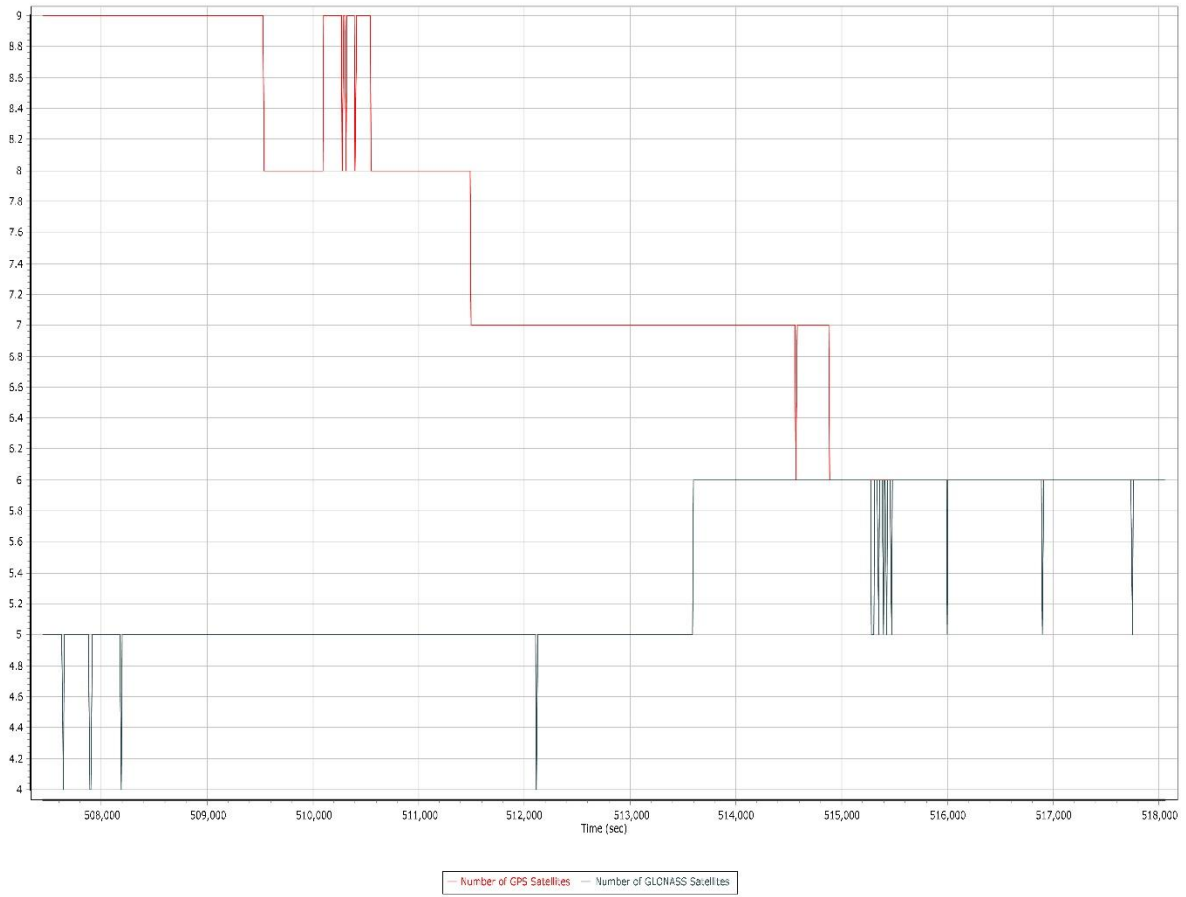


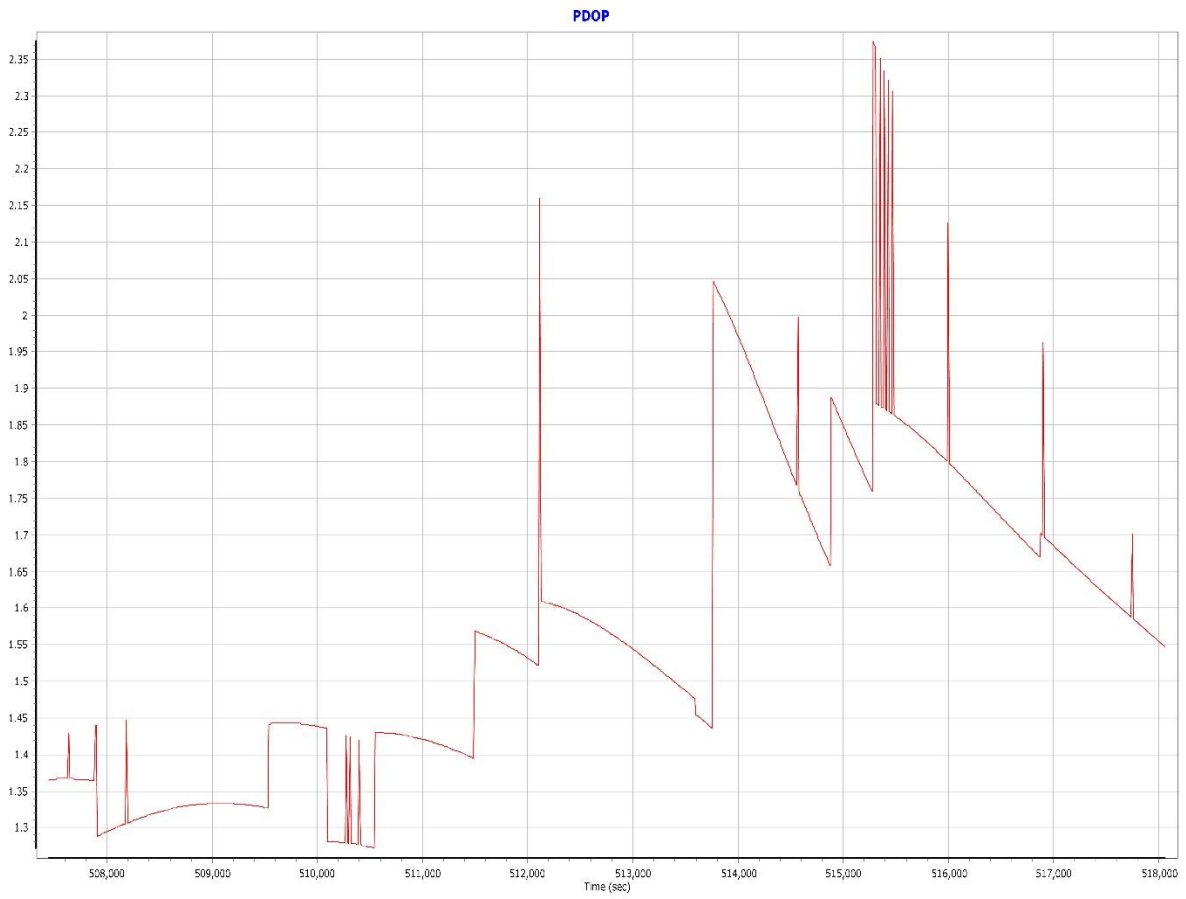
CAU18040B

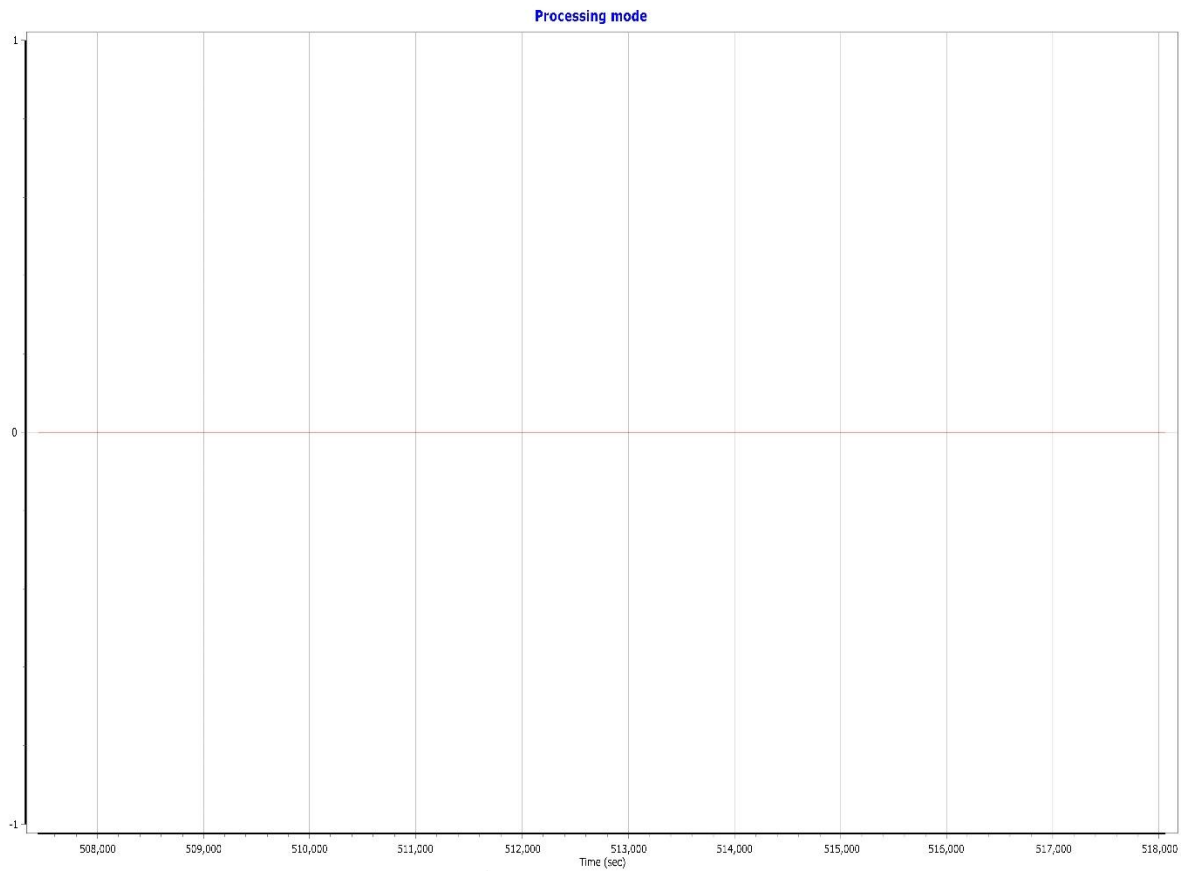






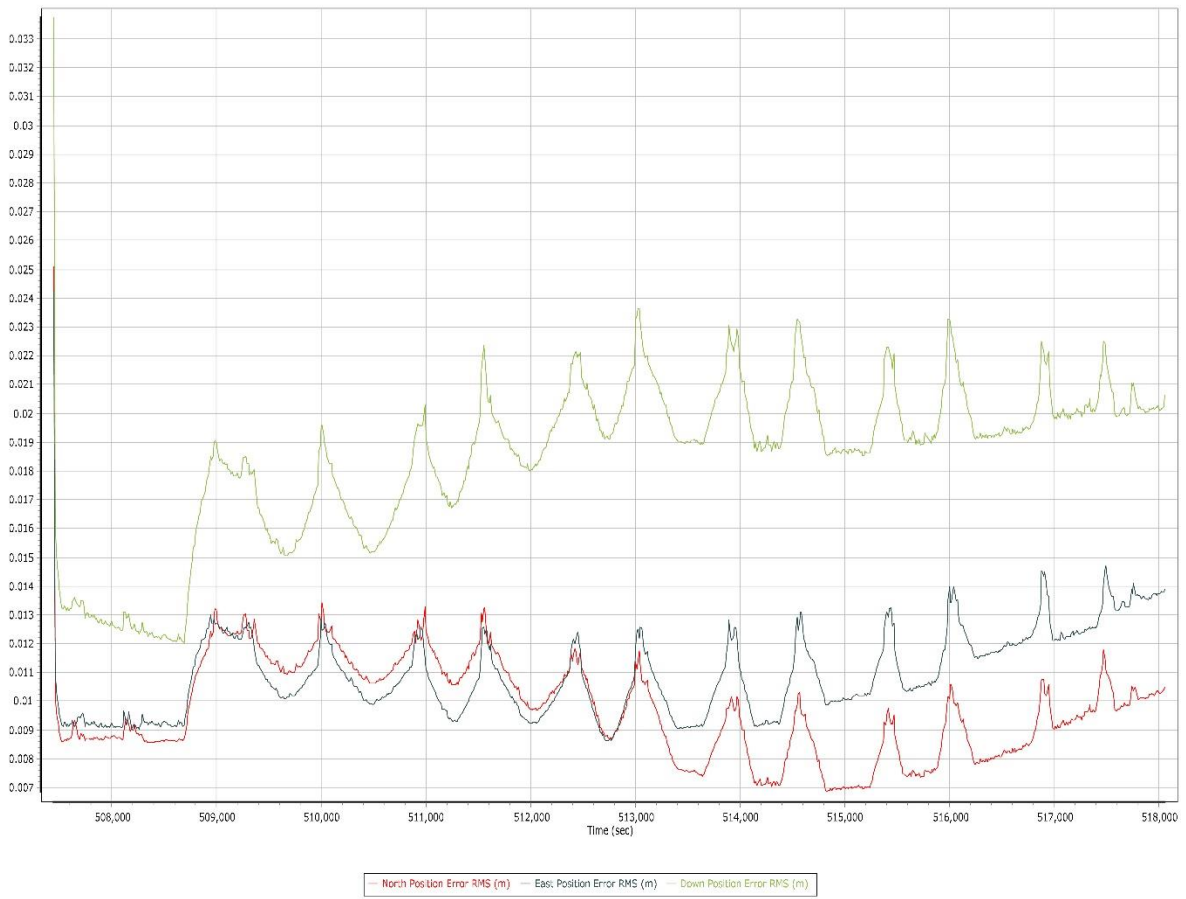


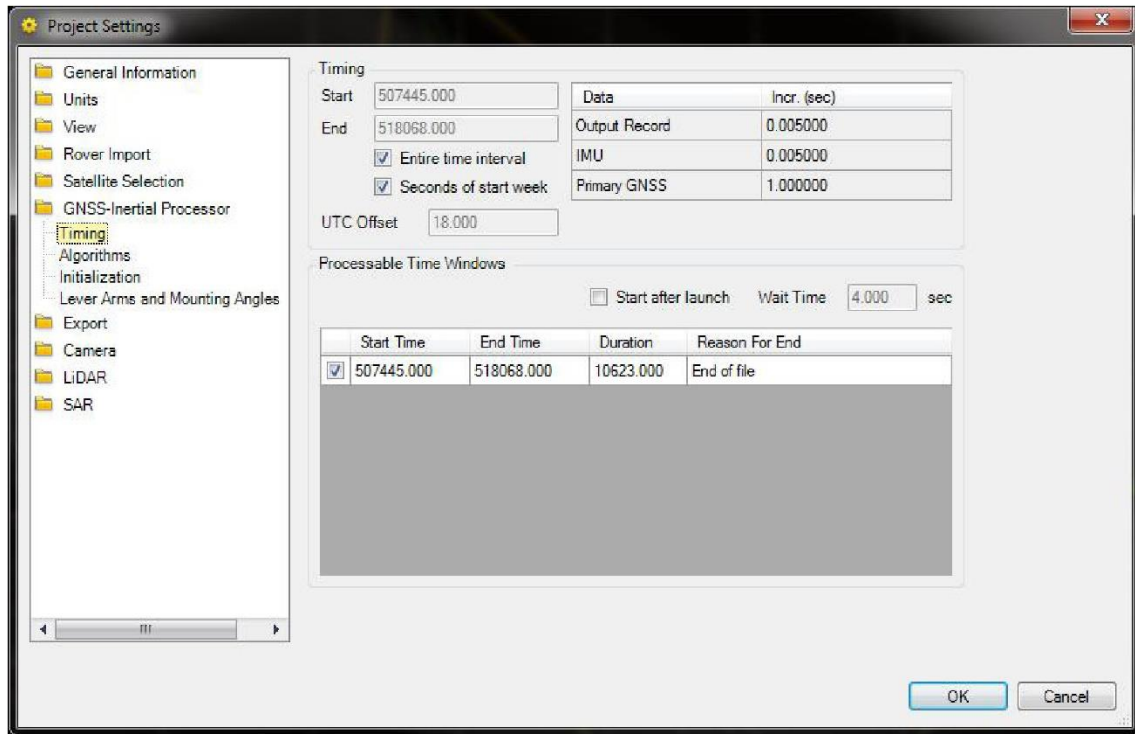


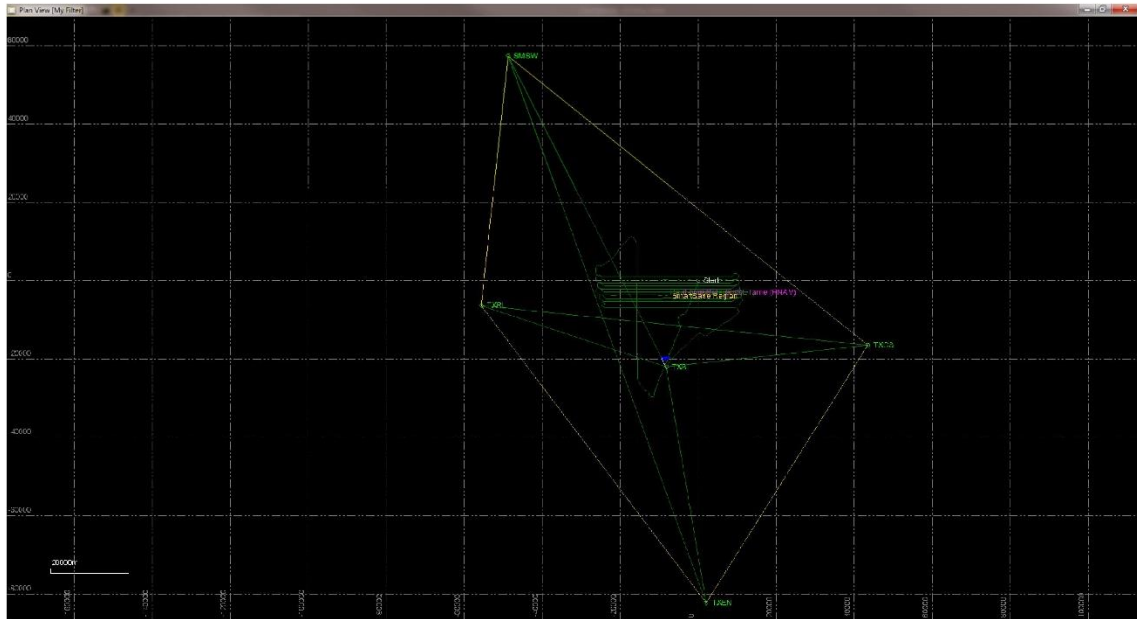


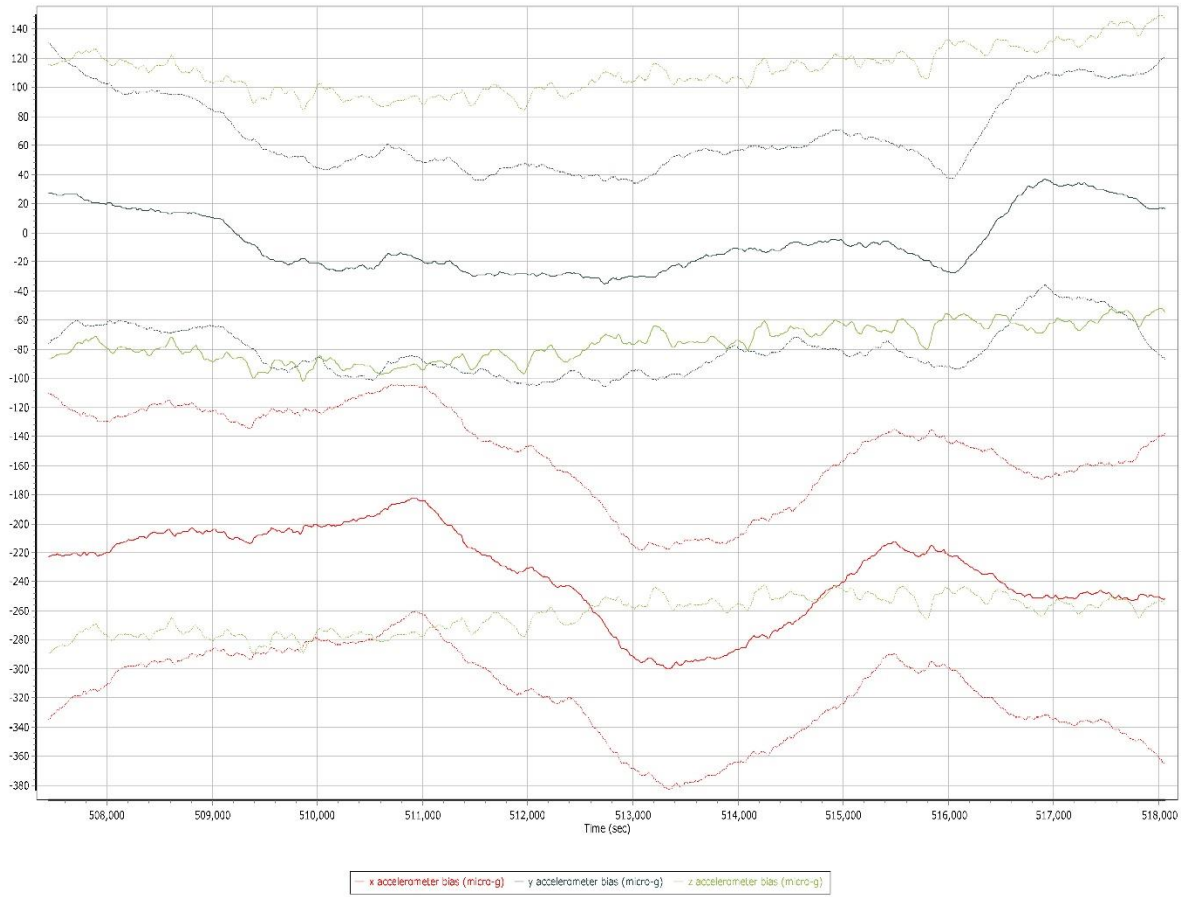
0 = Fixed NL, 1 = fixed WL, 2 = float, 3 = DGNSS, 4 = RTCM, 5 = IA PPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

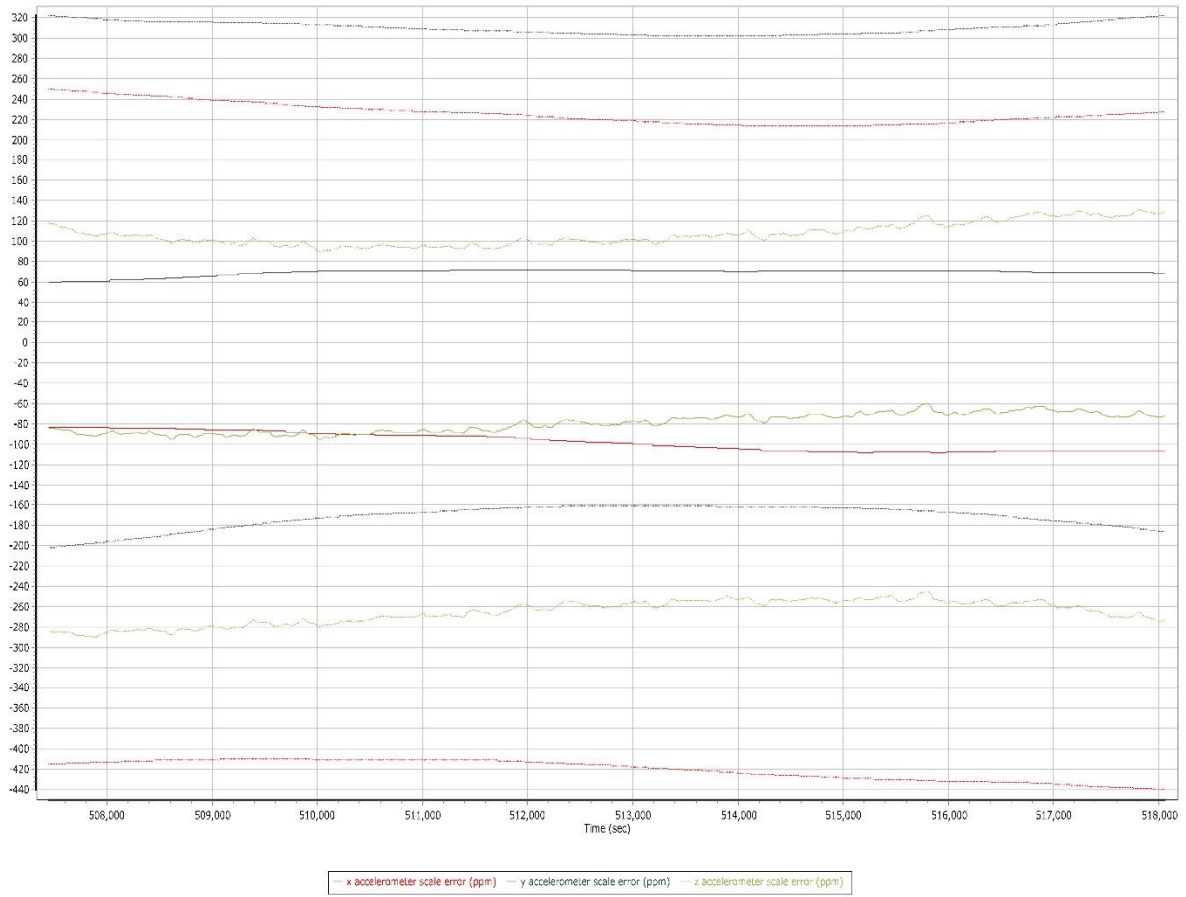


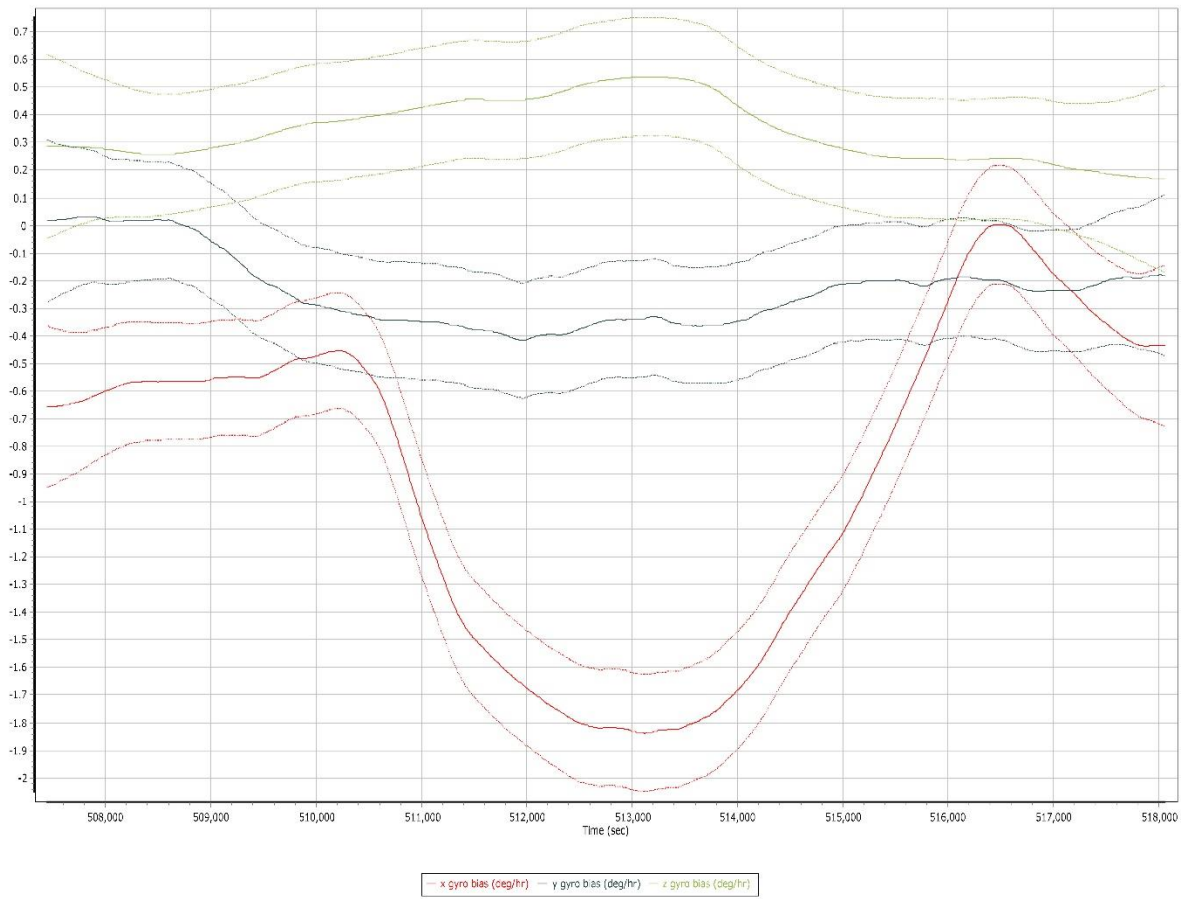


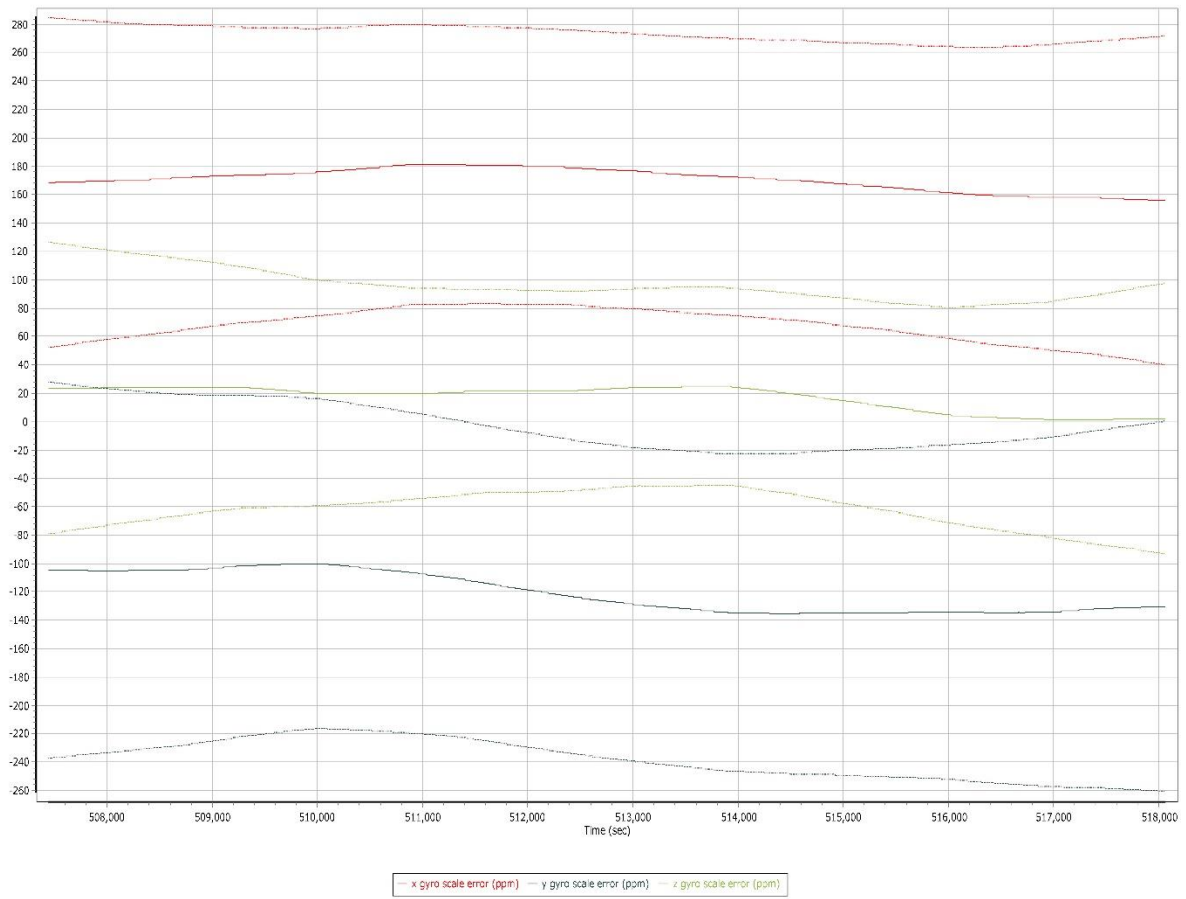




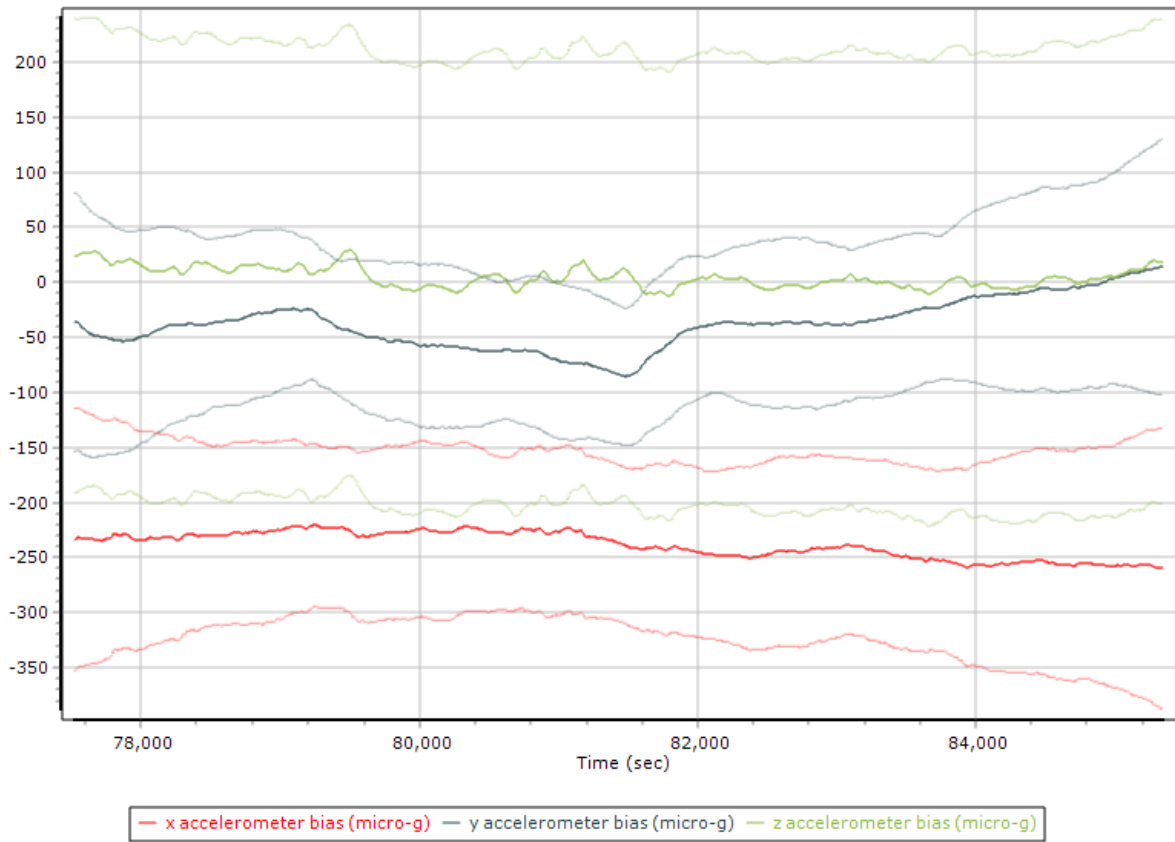


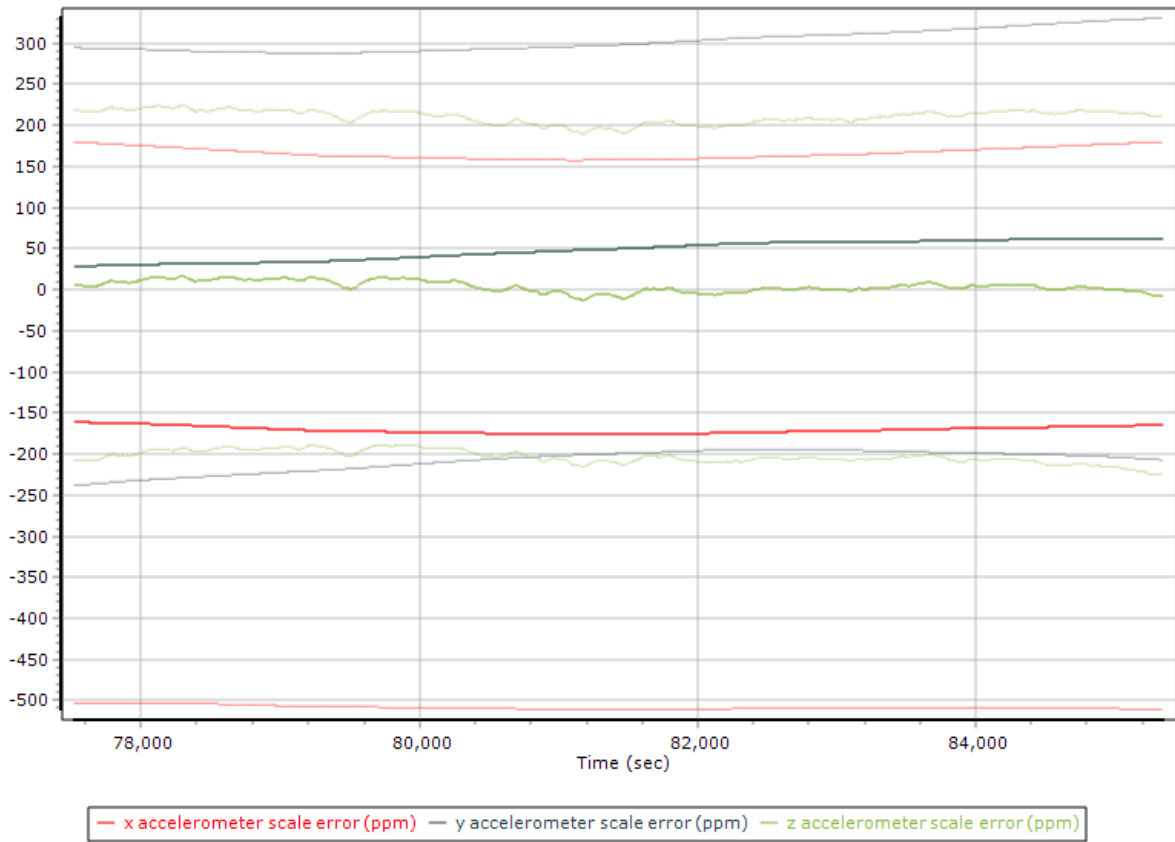


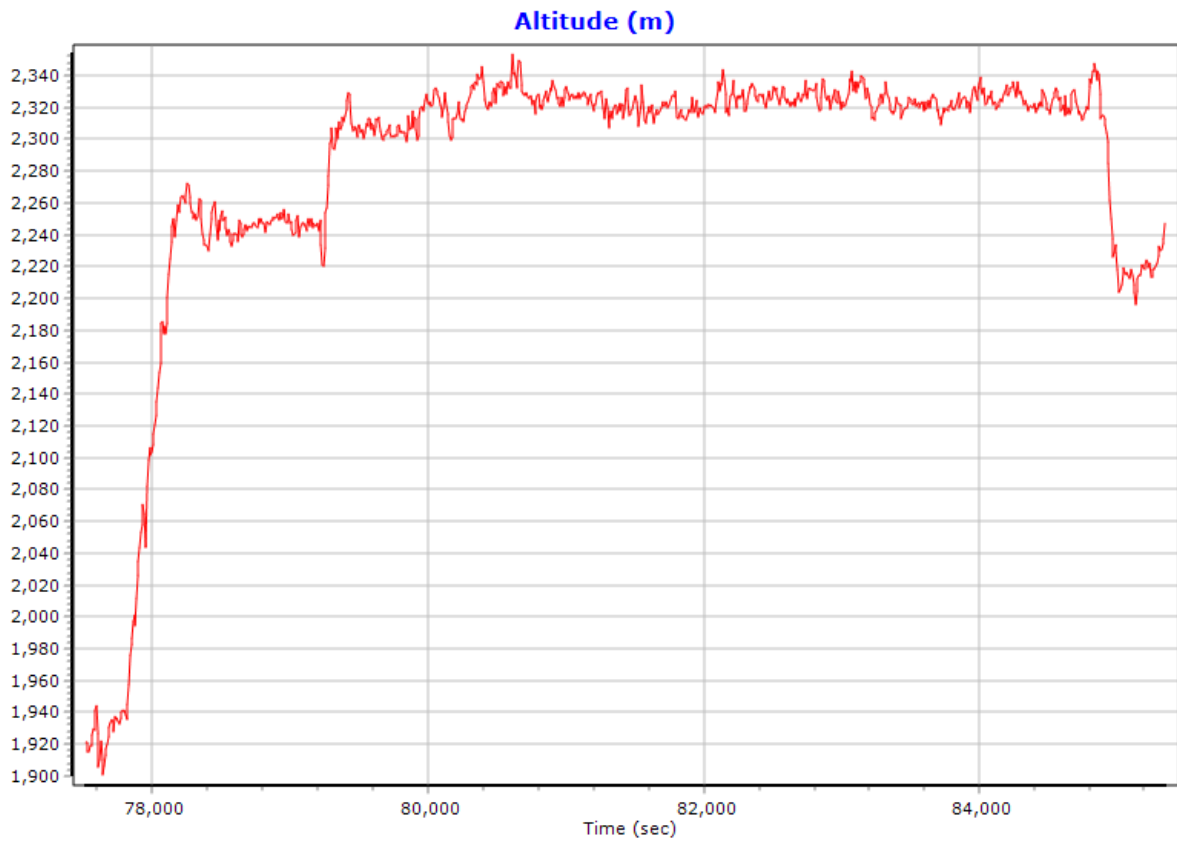


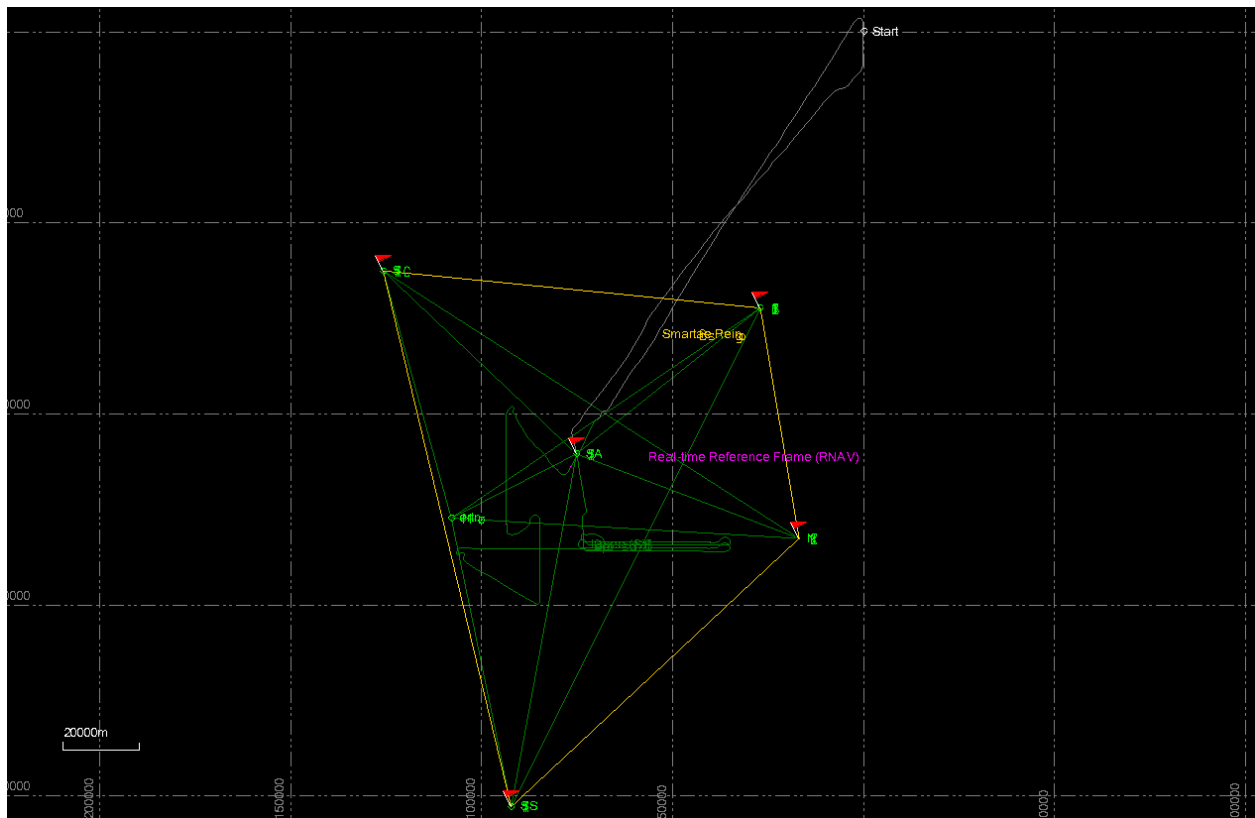
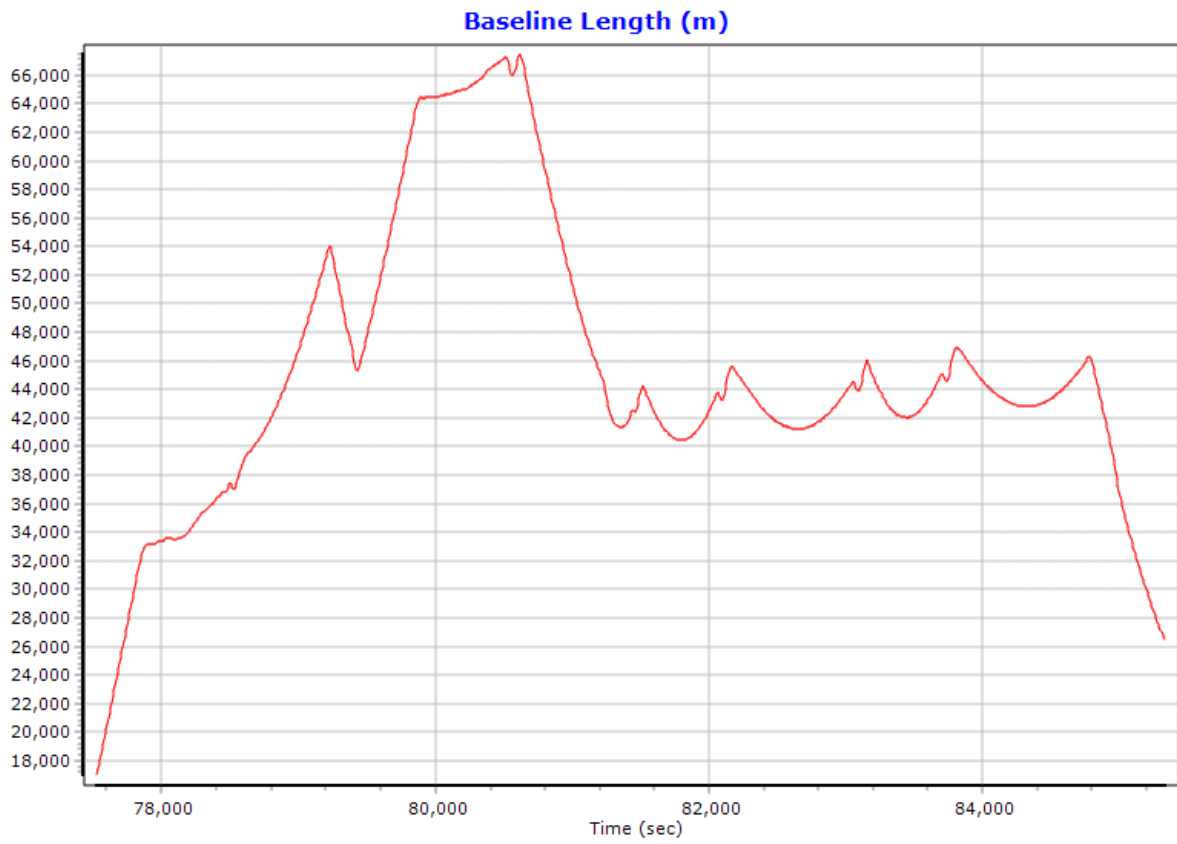


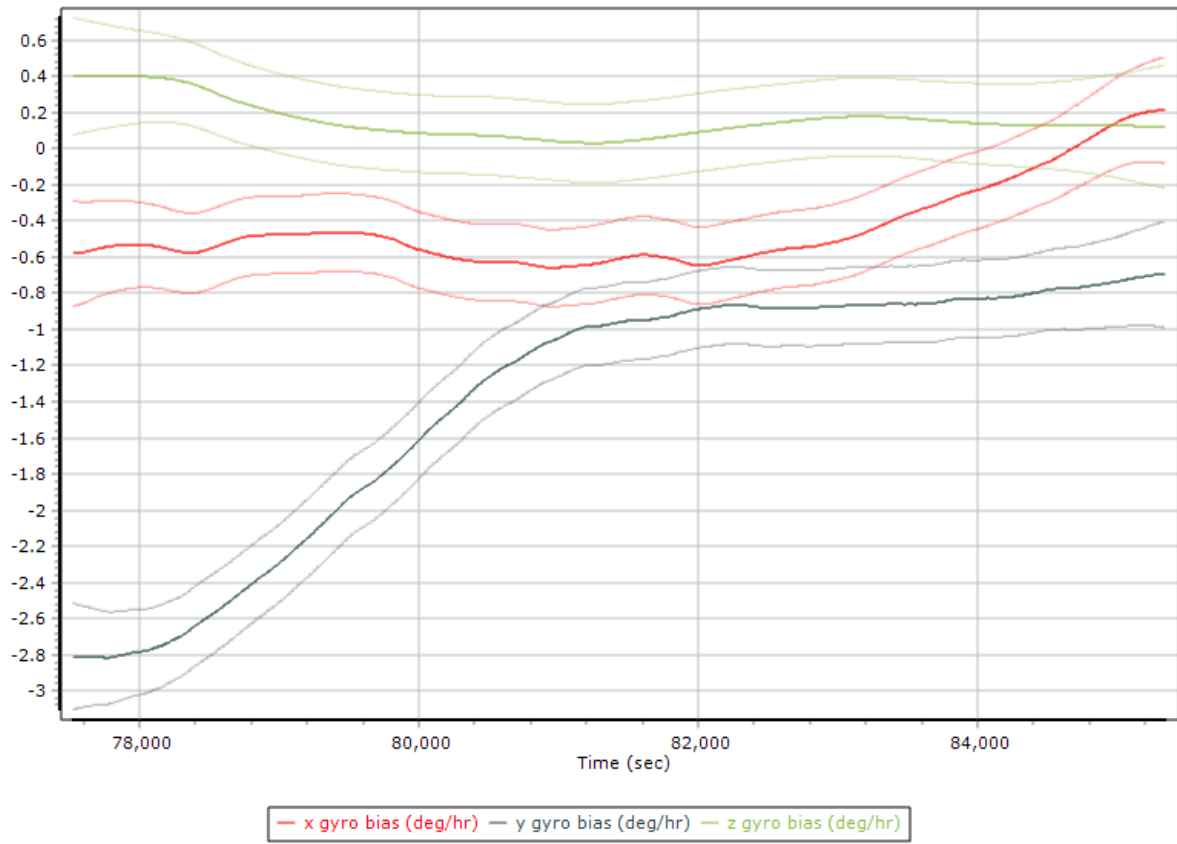
CAU18042A

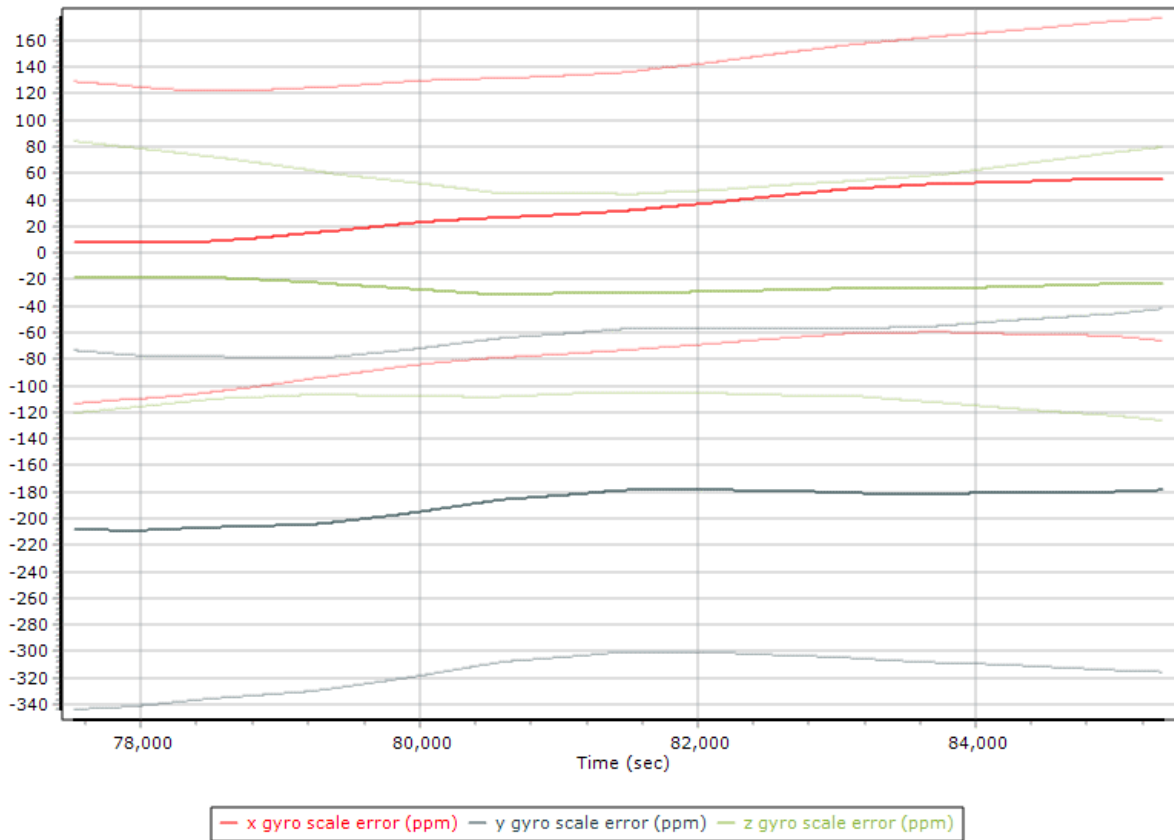












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

Aircraft to Reference Mounting Angles

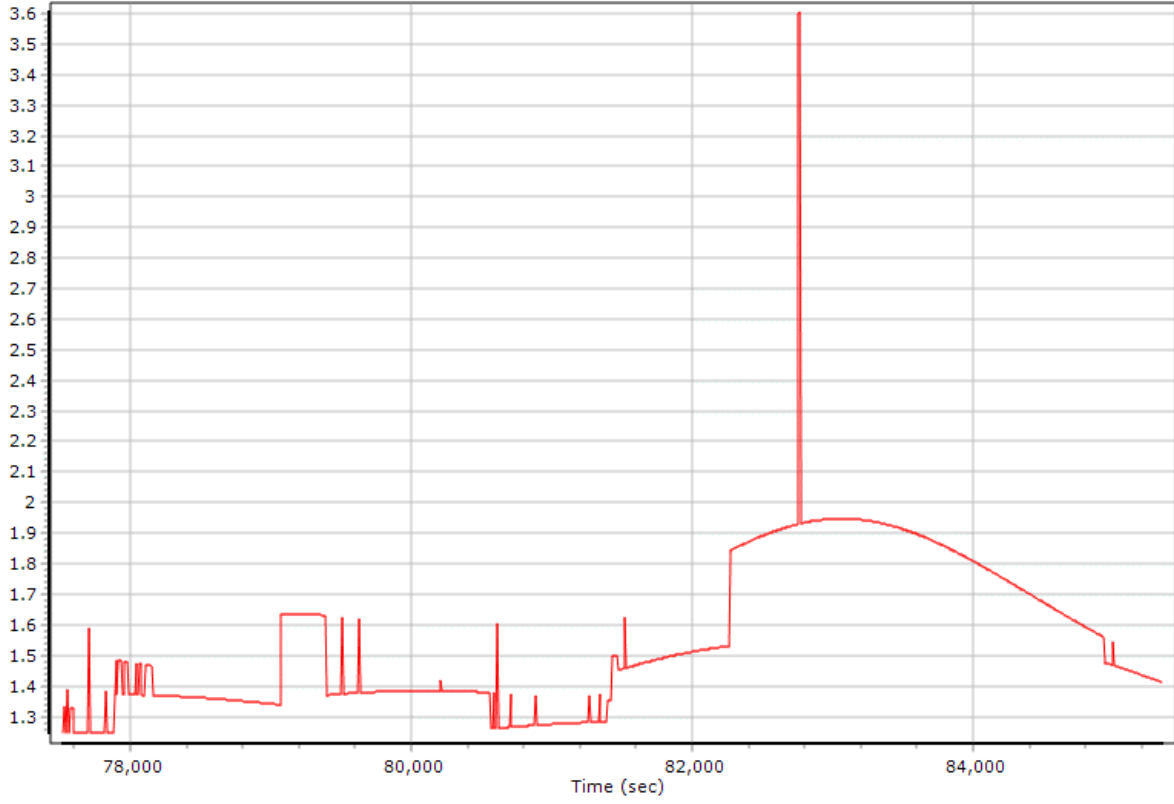
X:

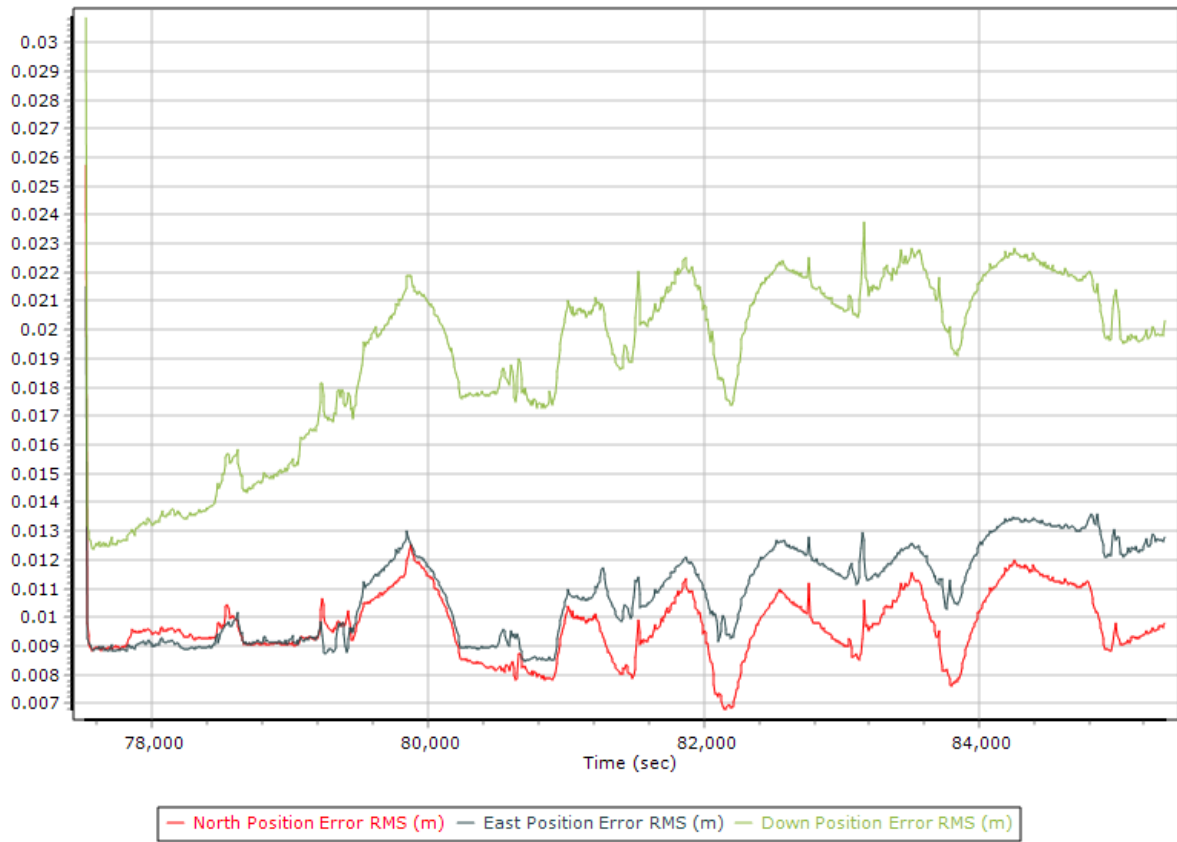
Y:

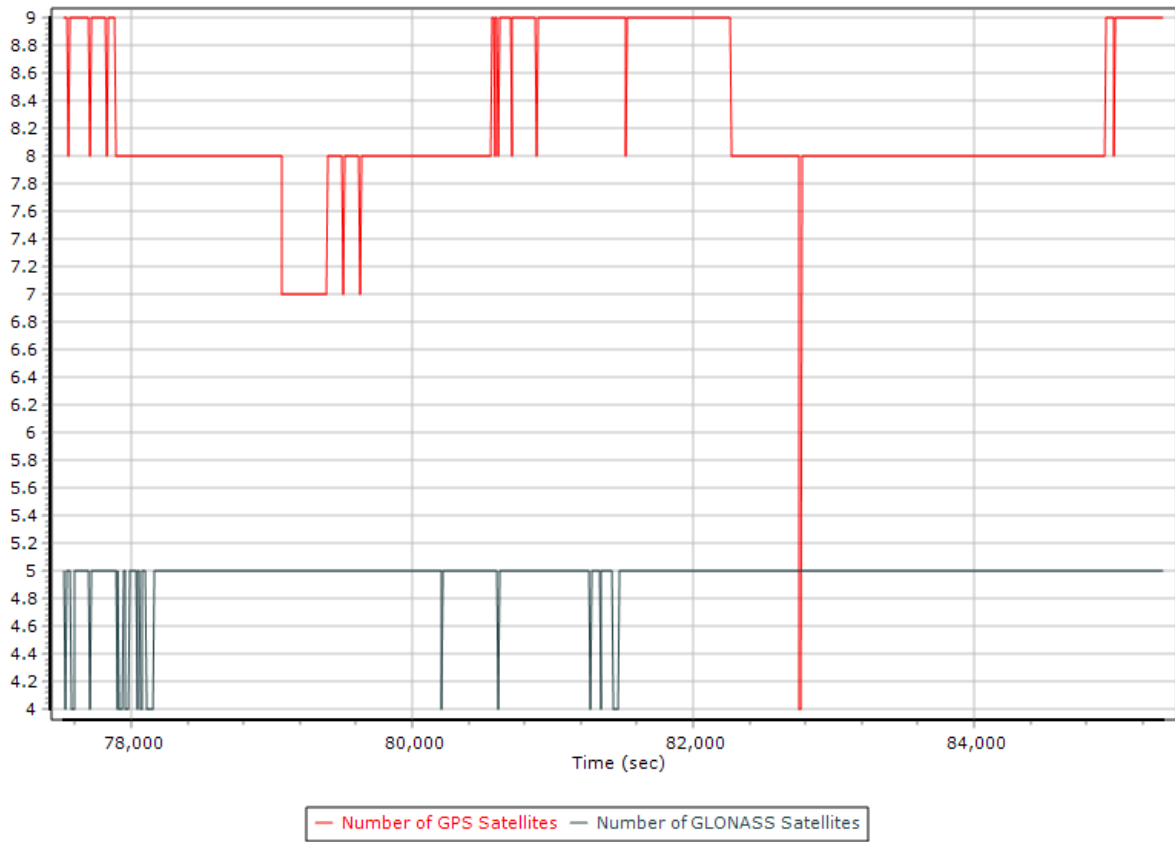
Z:

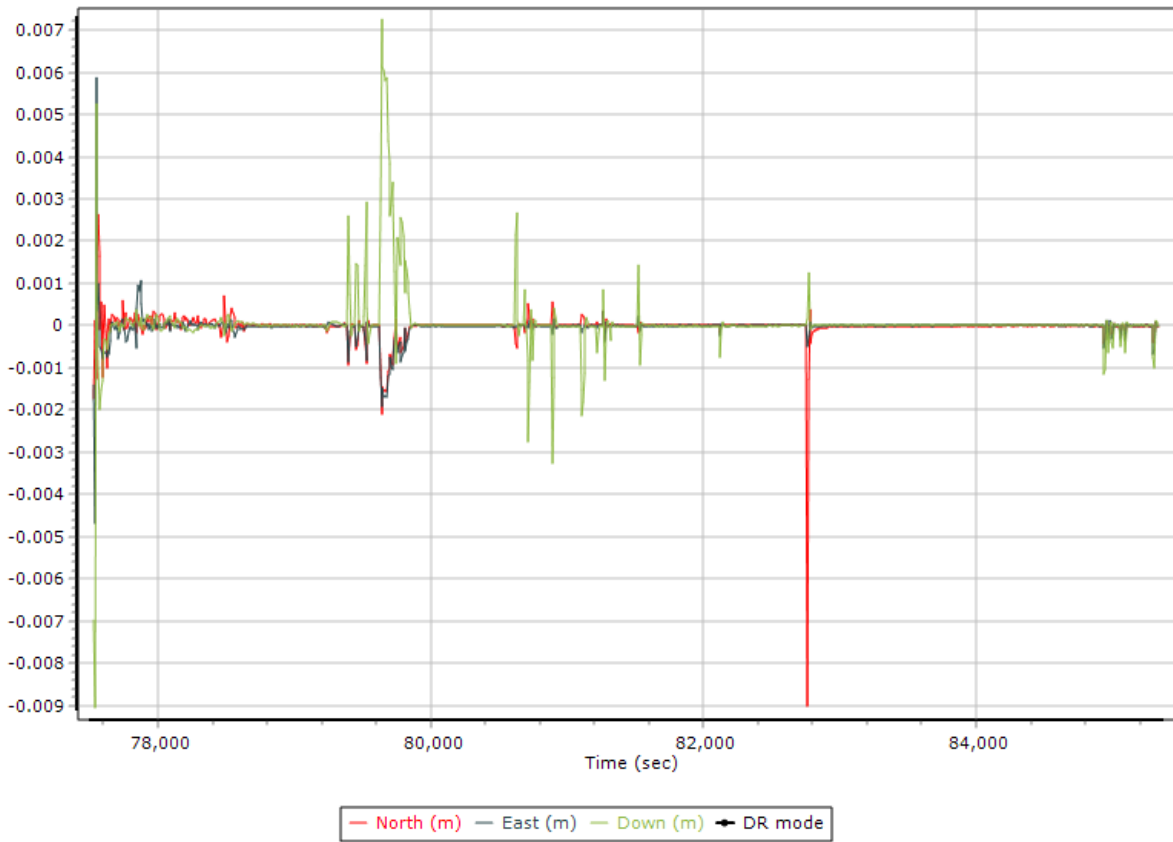
OK Cancel

PDOP









Project Settings [X]

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

Timing

Start: 74548.000
 End: 88218.000
 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

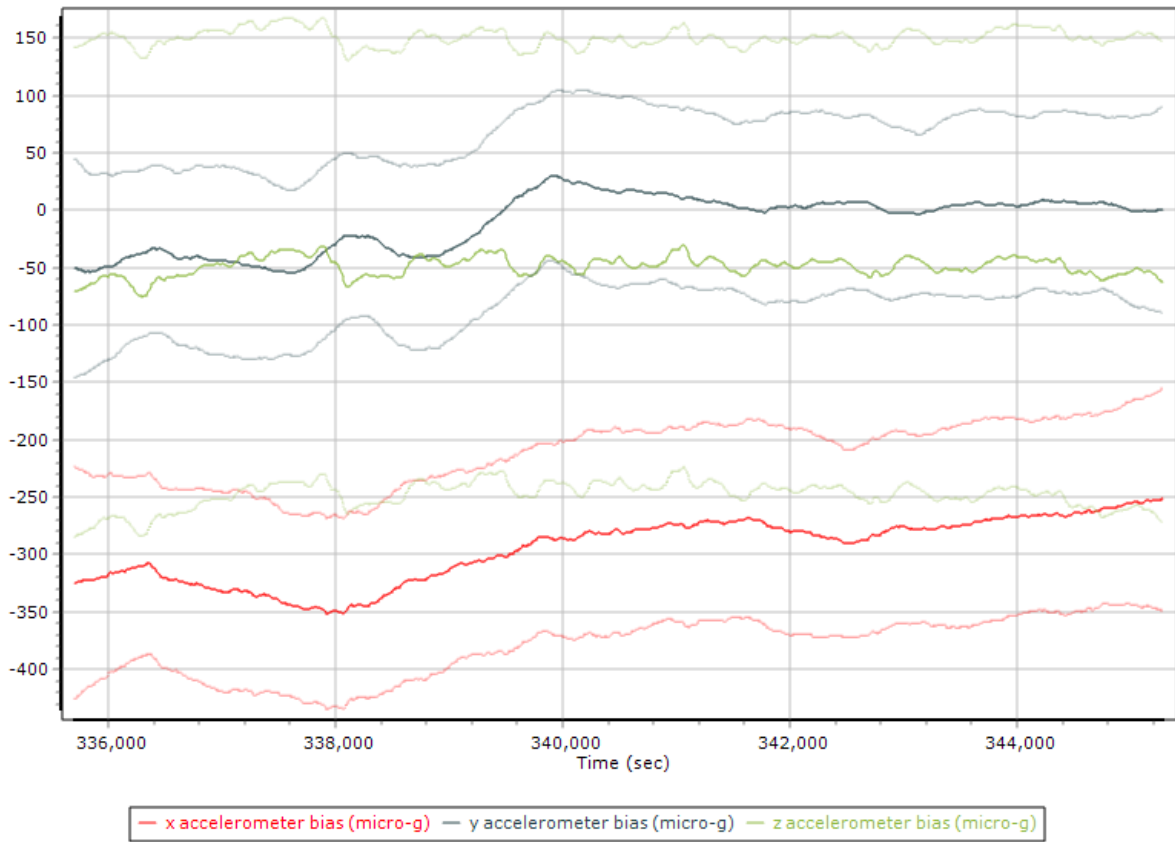
Processable Time Windows

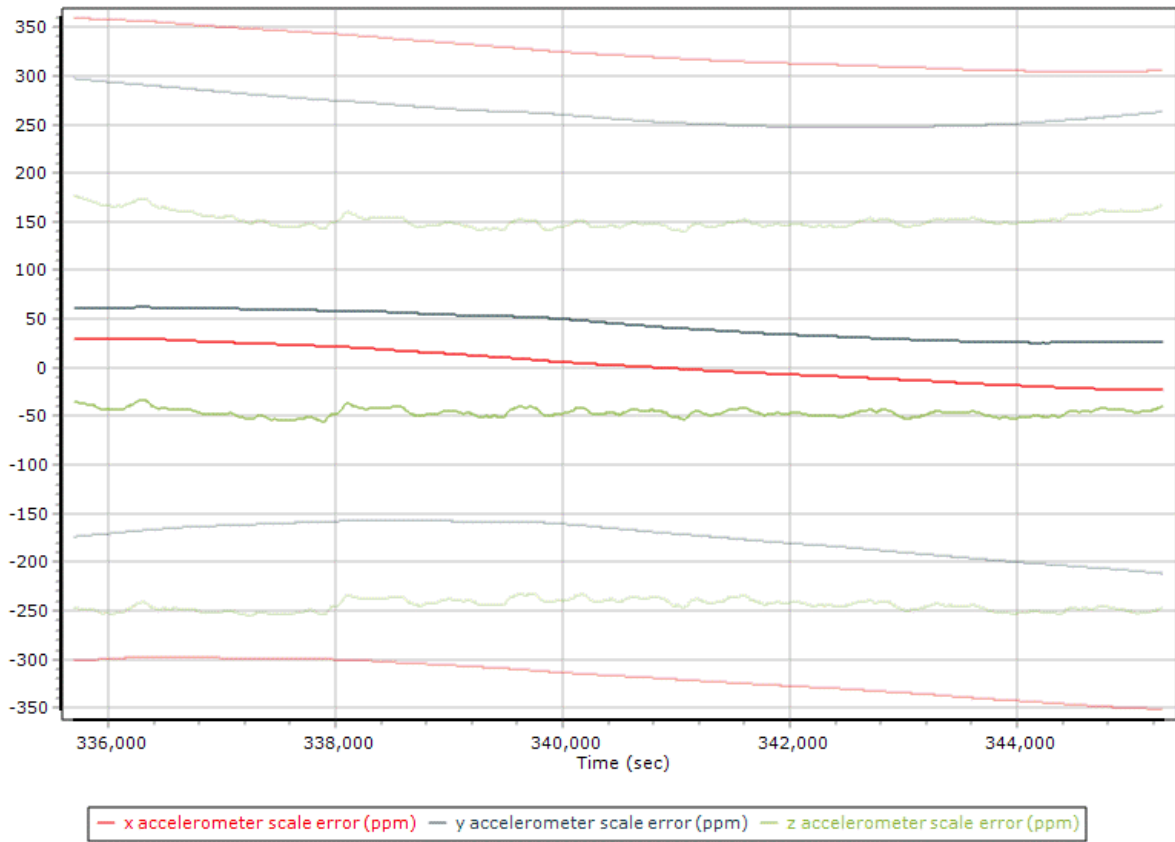
Start after launch Wait Time: 4.000 sec

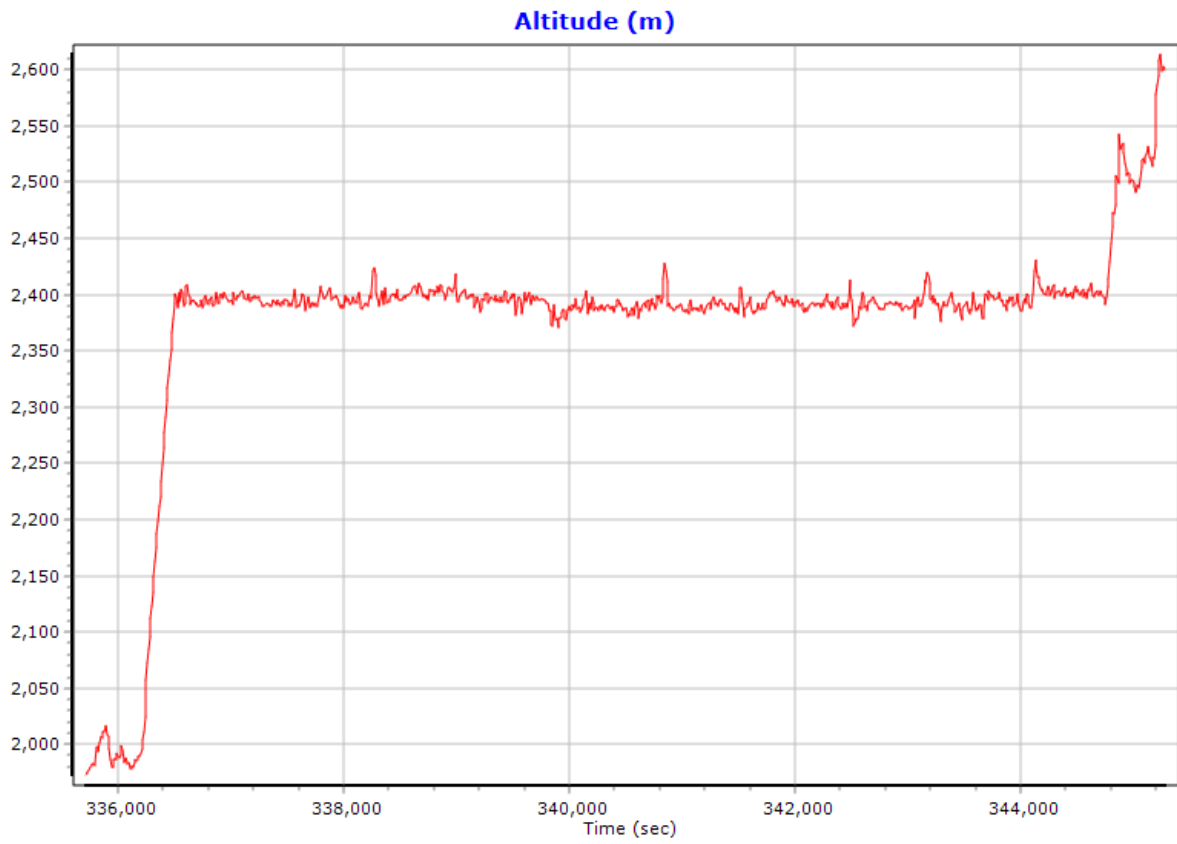
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	74548.000	88218.000	13670.000	End of file

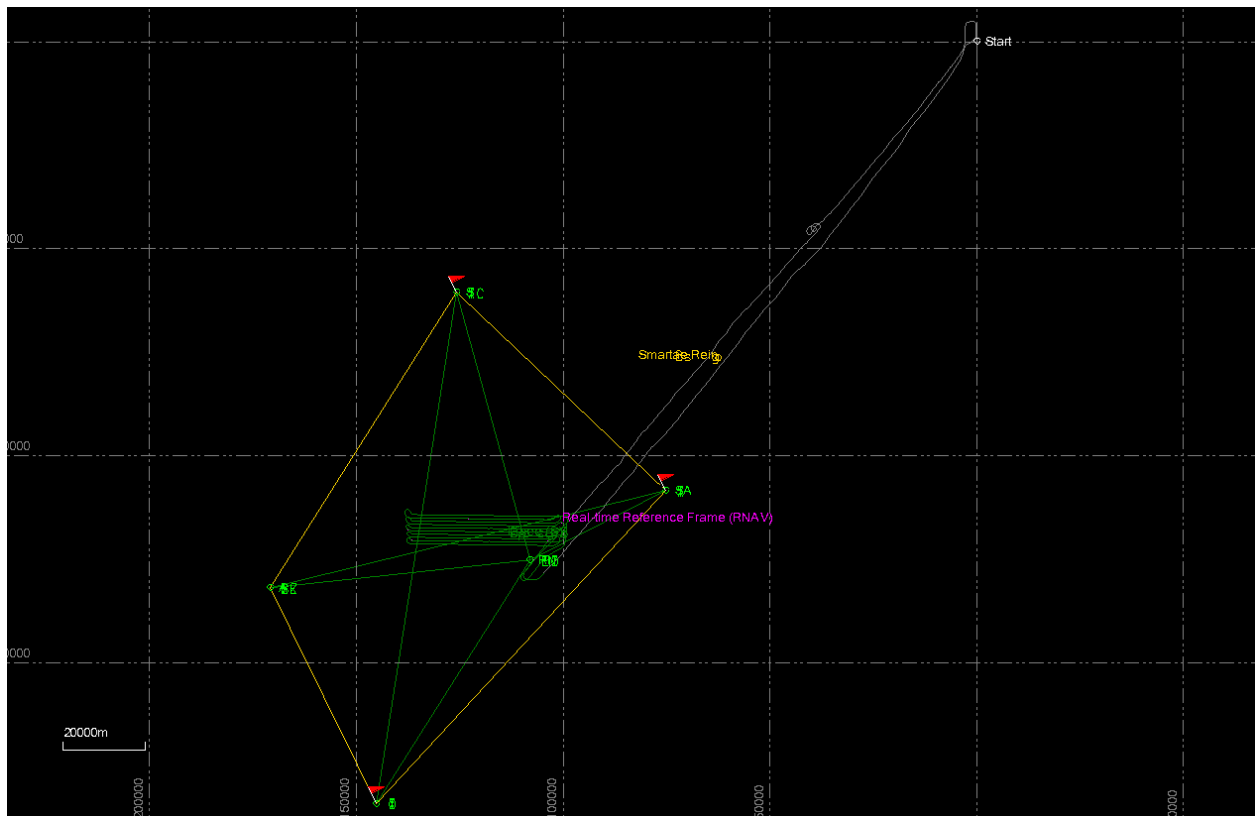
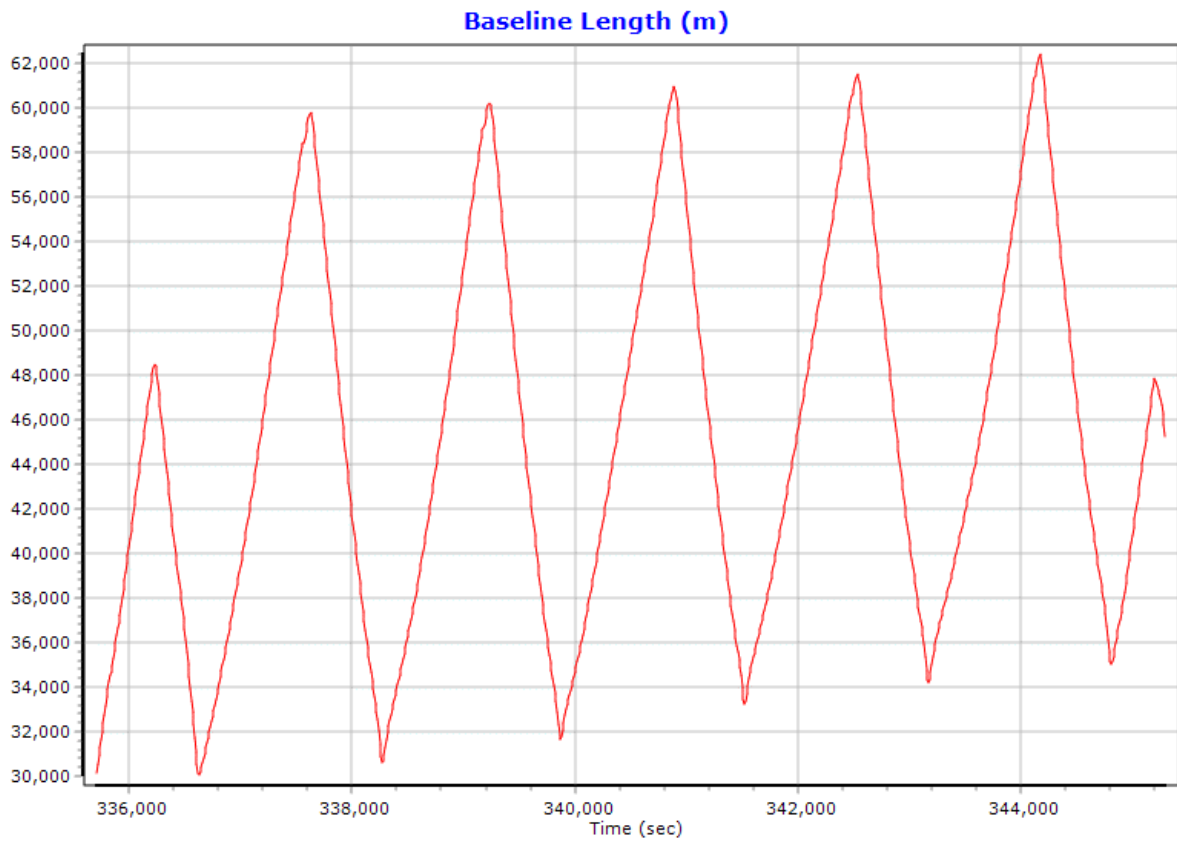
OK Cancel

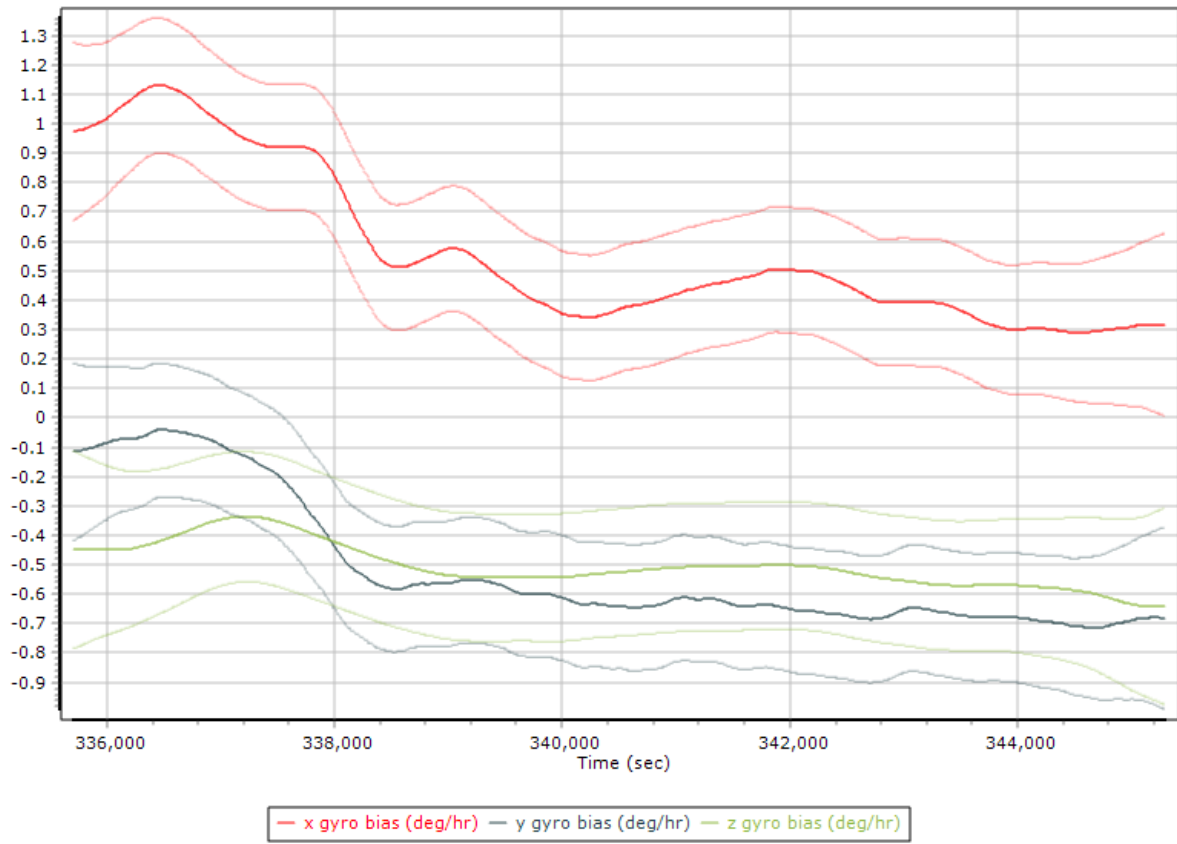
CAU18045A

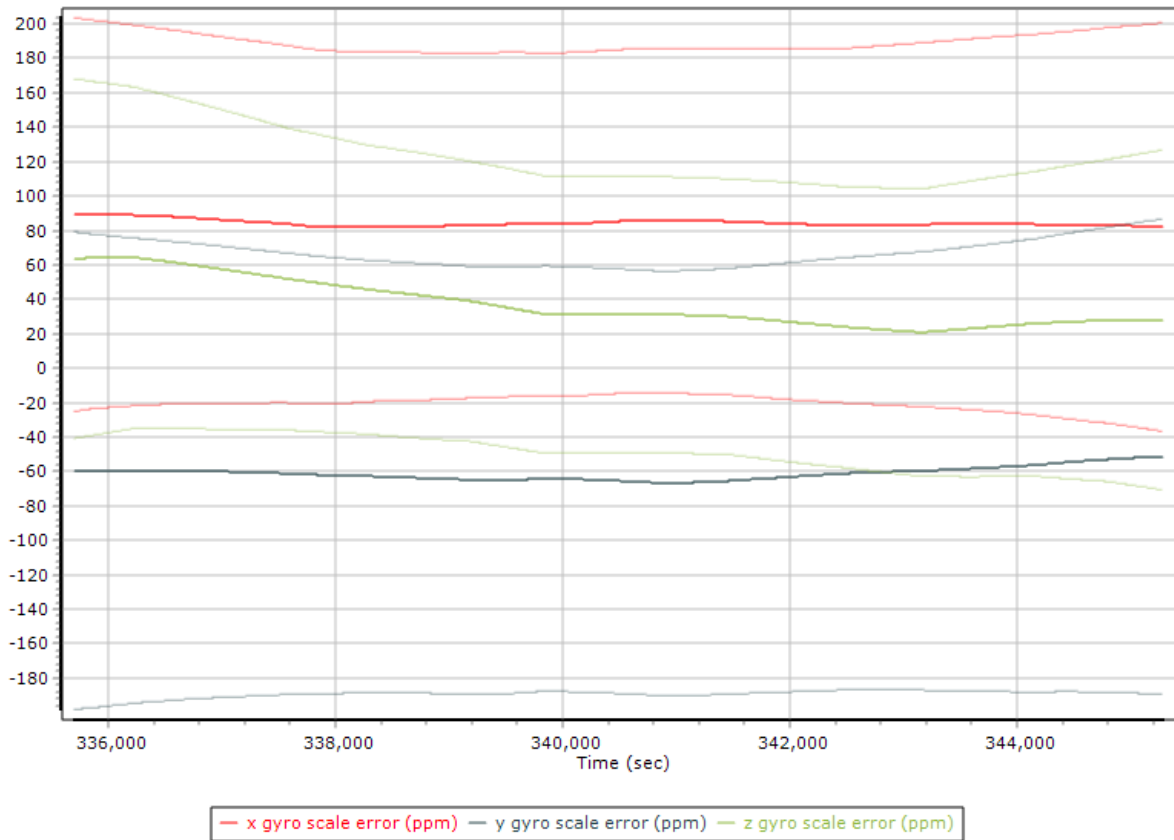












Project Settings [X]

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

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

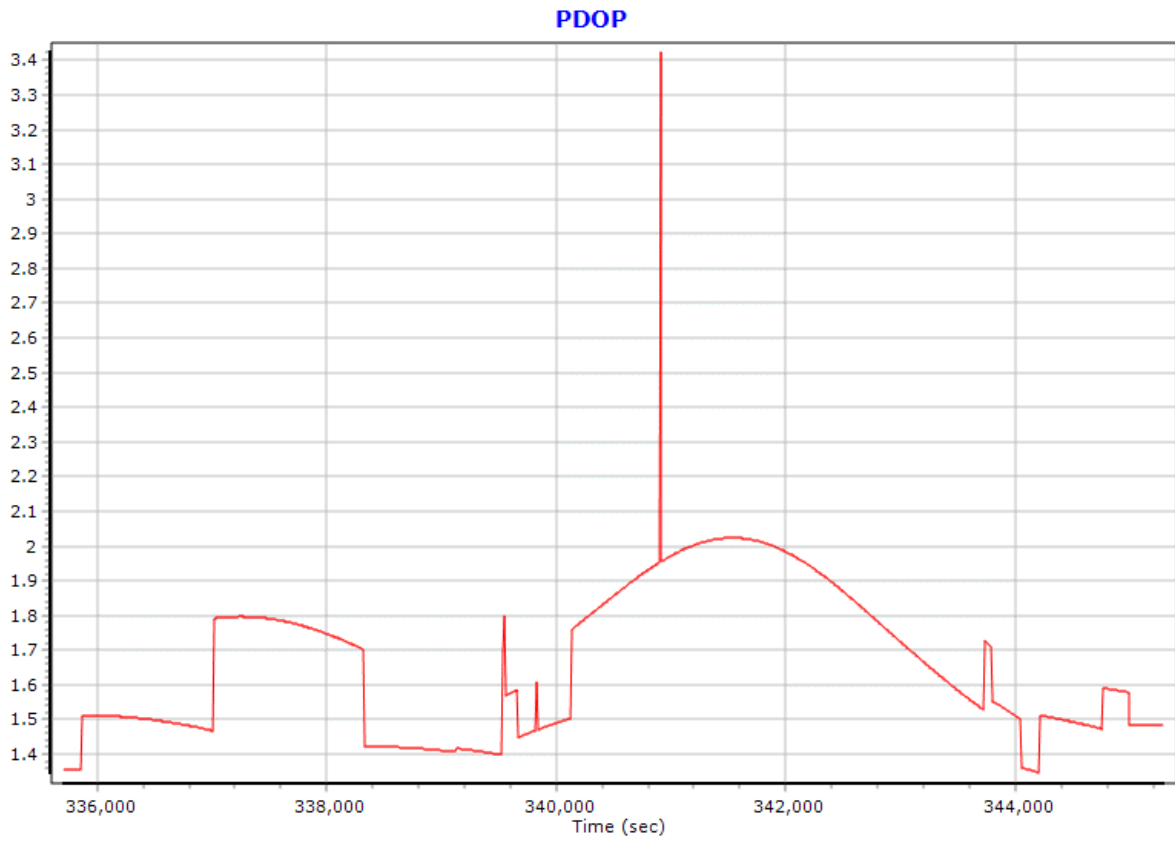
Aircraft to Reference Mounting Angles

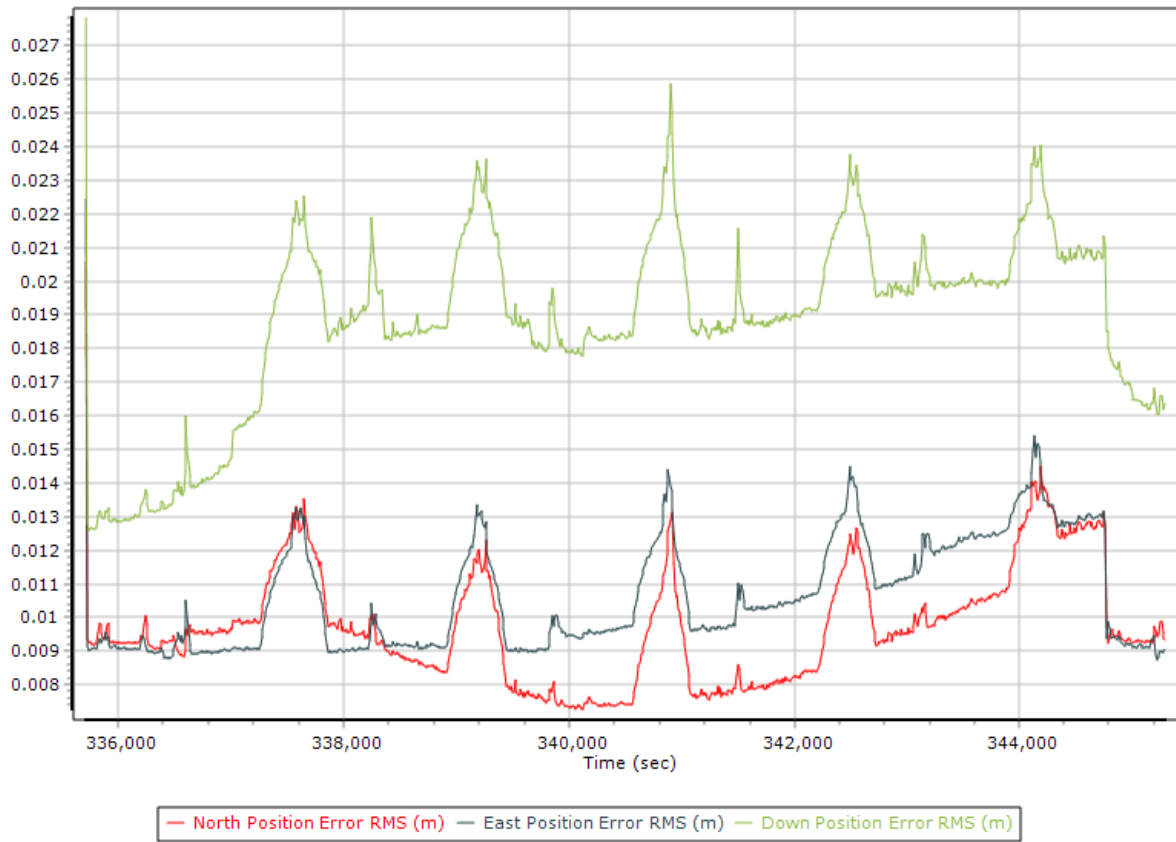
X:

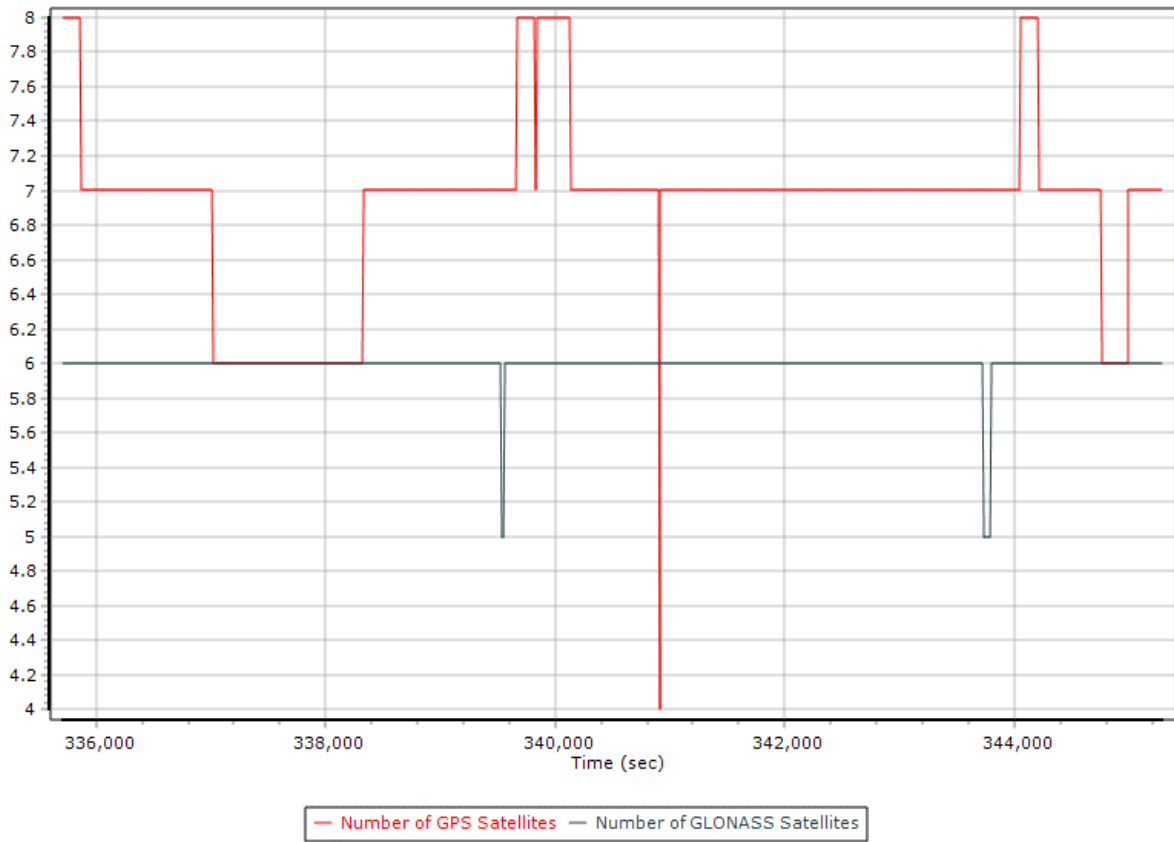
Y:

Z:

OK Cancel









Project Settings

- 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: 330588.000 Data Incr. (sec)

End: 347992.000 Output Record 0.005000

Entire time interval IMU 0.005000

Seconds of start week Primary GNSS 1.000000

UTC Offset: 18.000

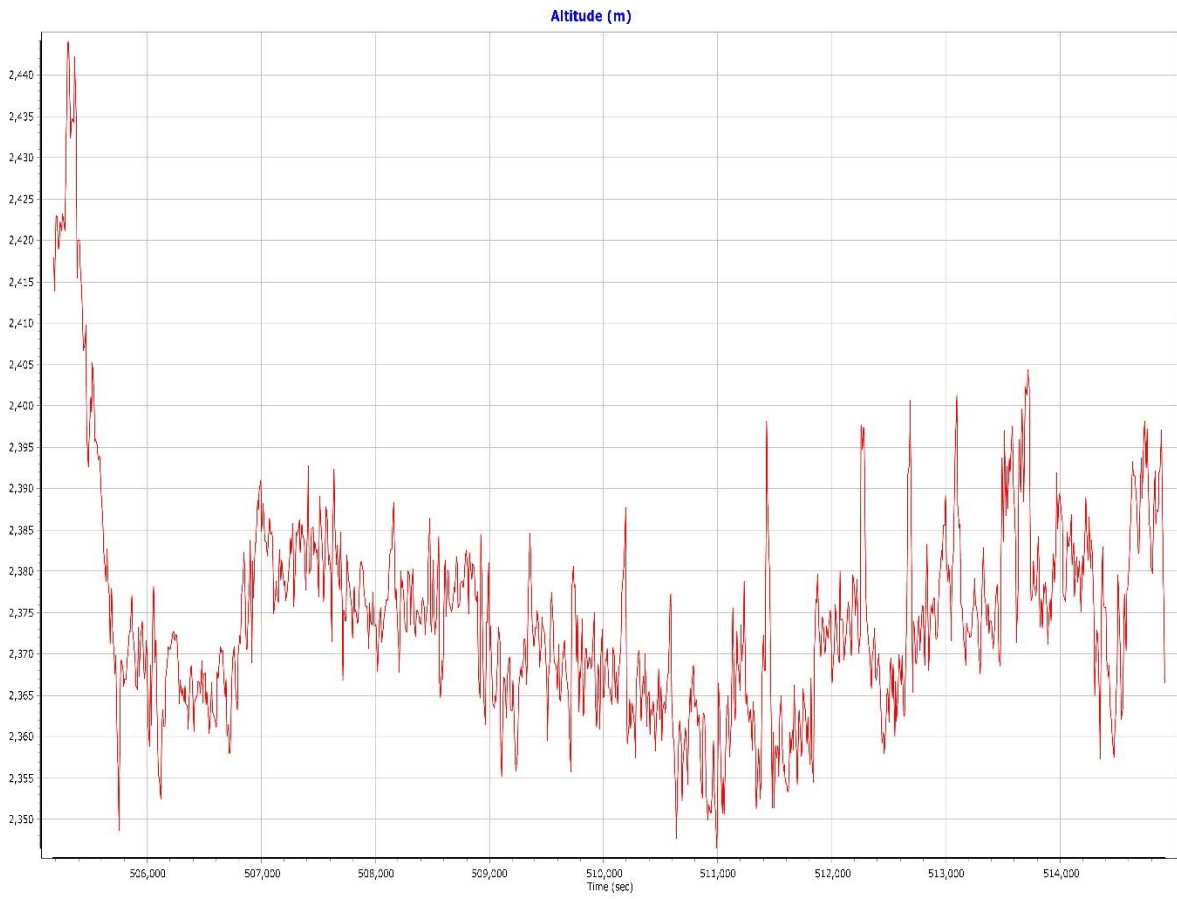
Processable Time Windows

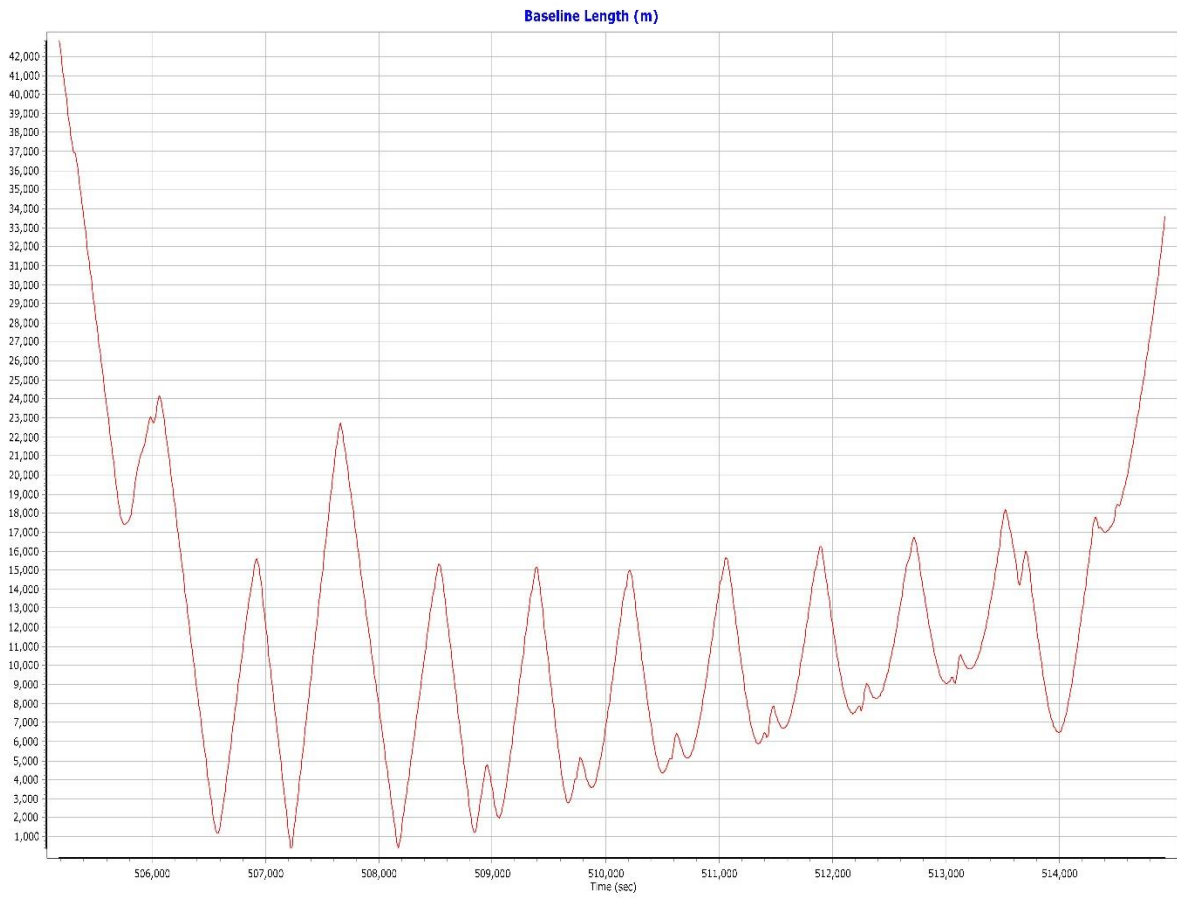
Start after launch Wait Time: 4.000 sec

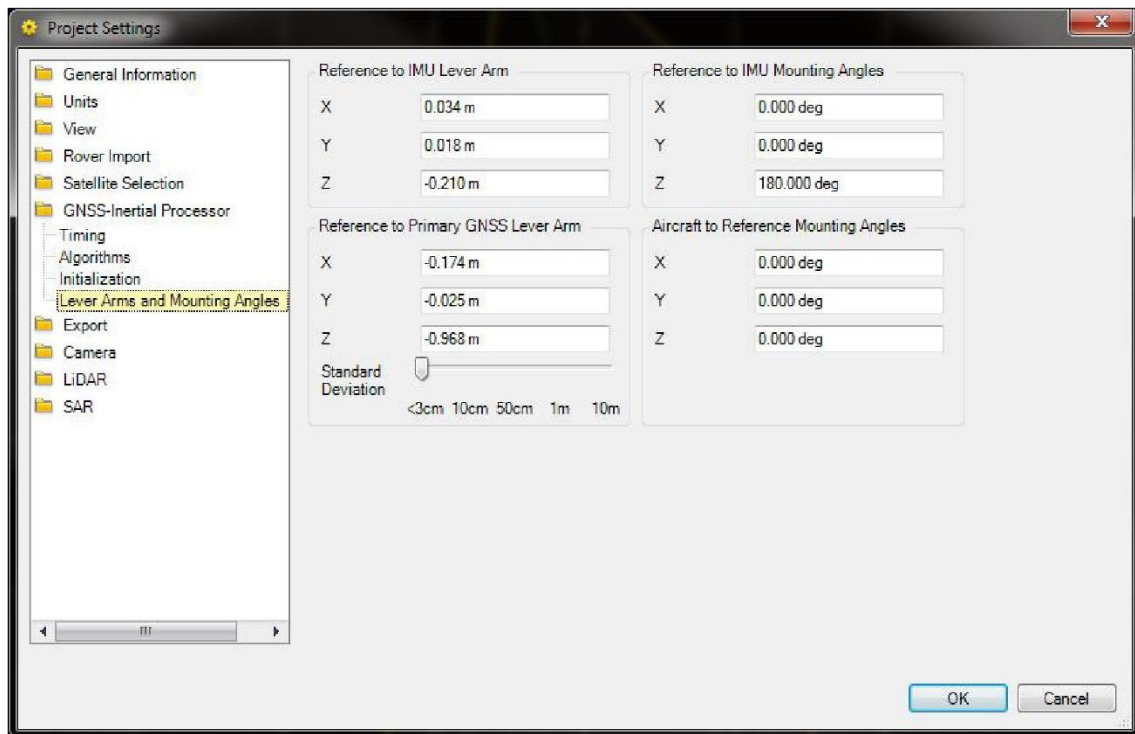
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	330588.000	347992.000	17404.000	End of file

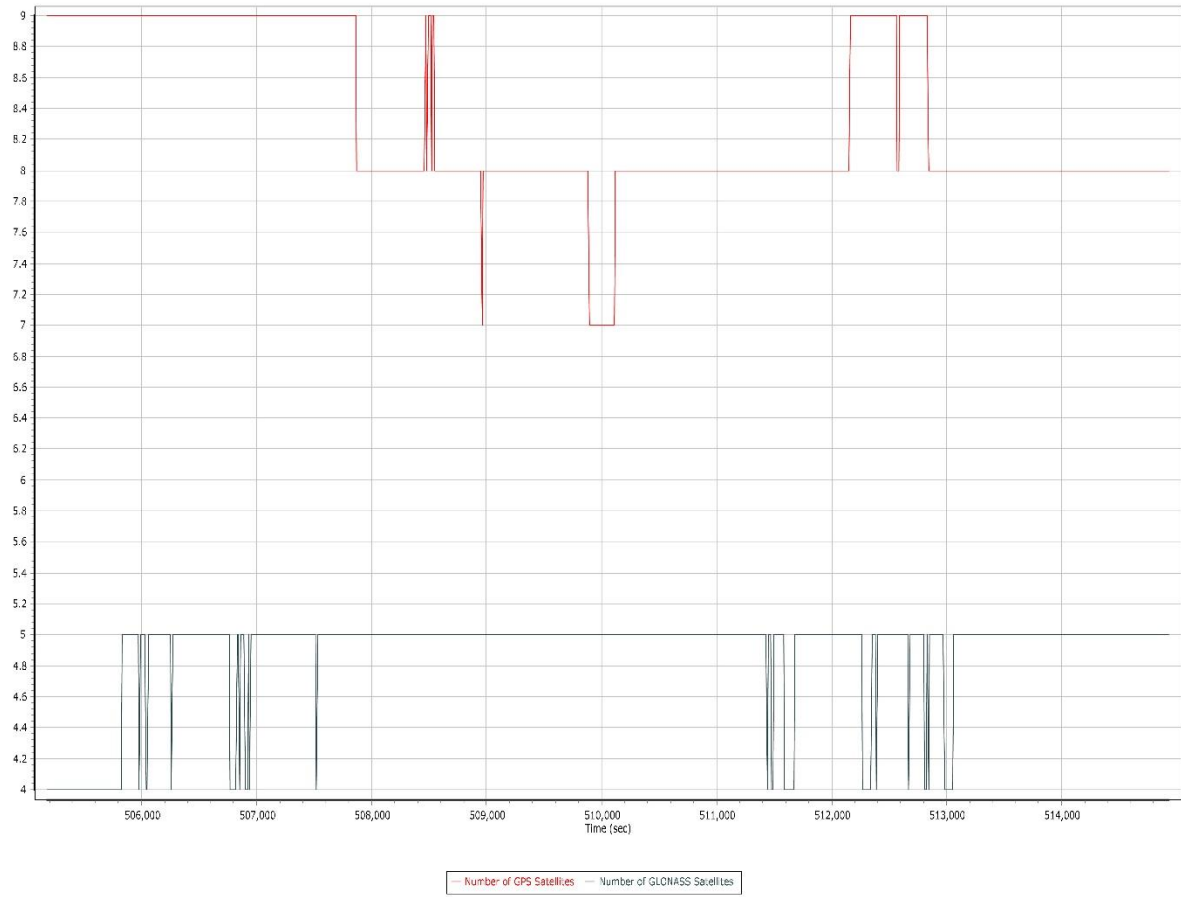
OK Cancel

CAU18047A

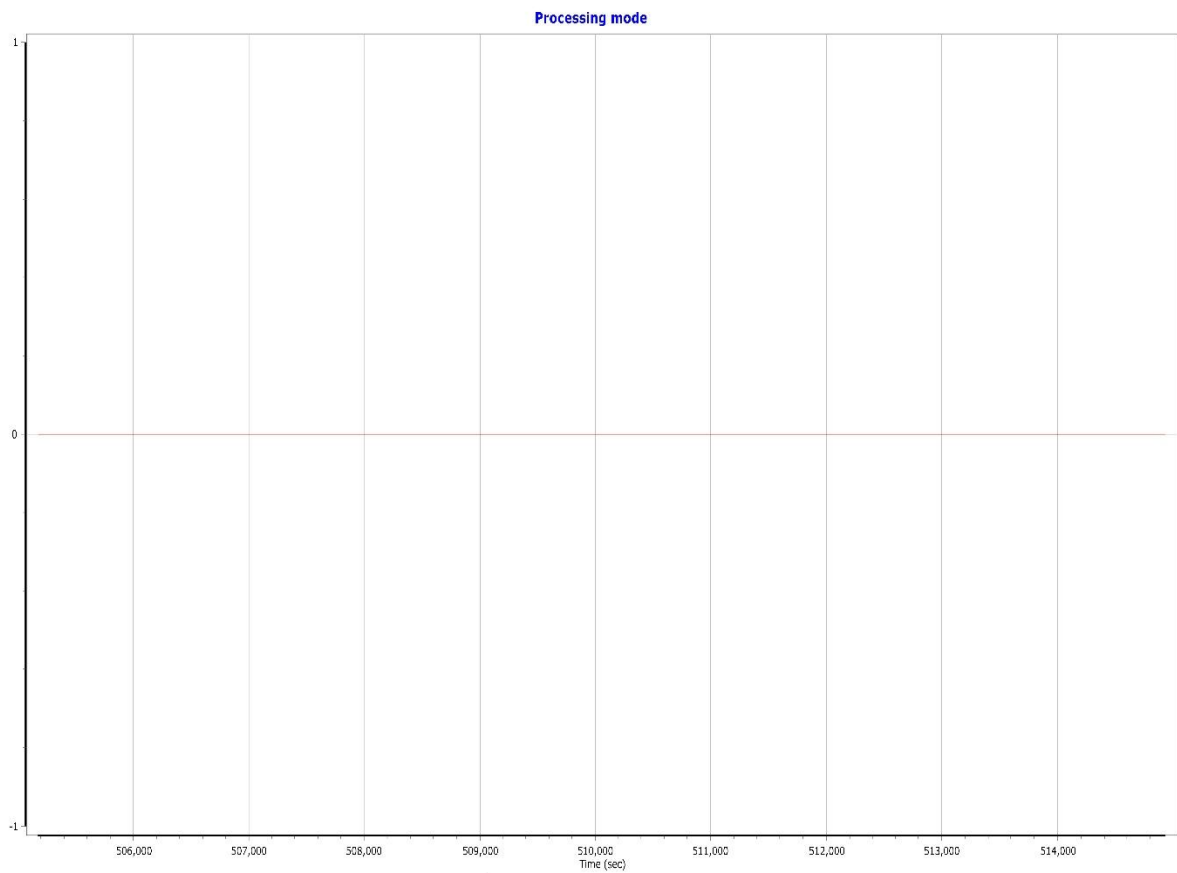




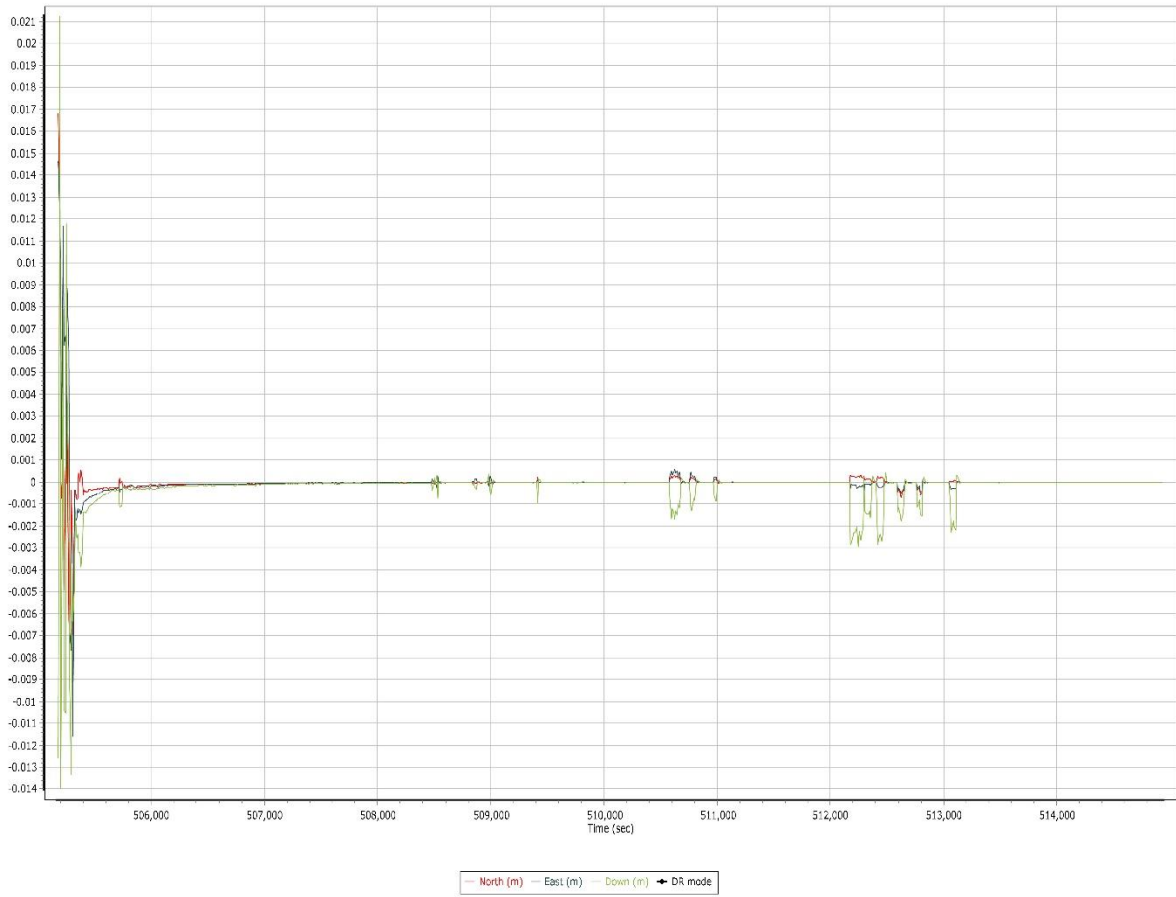


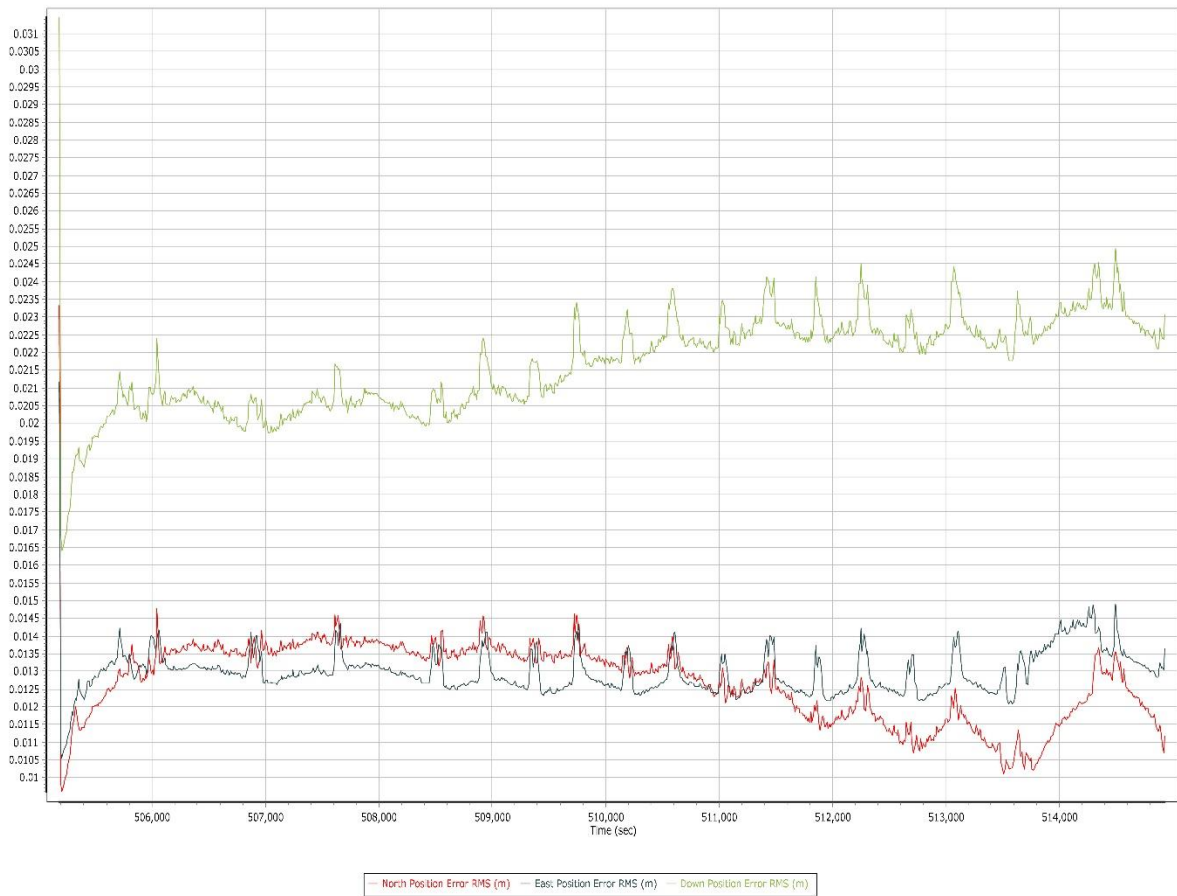


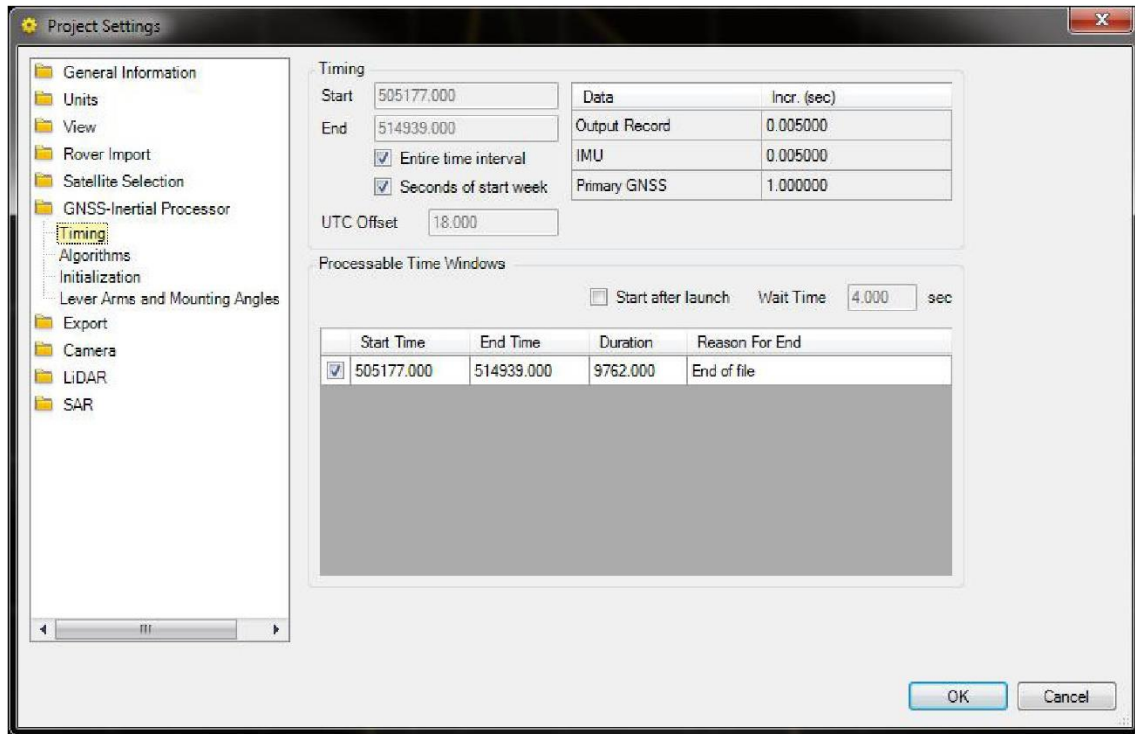


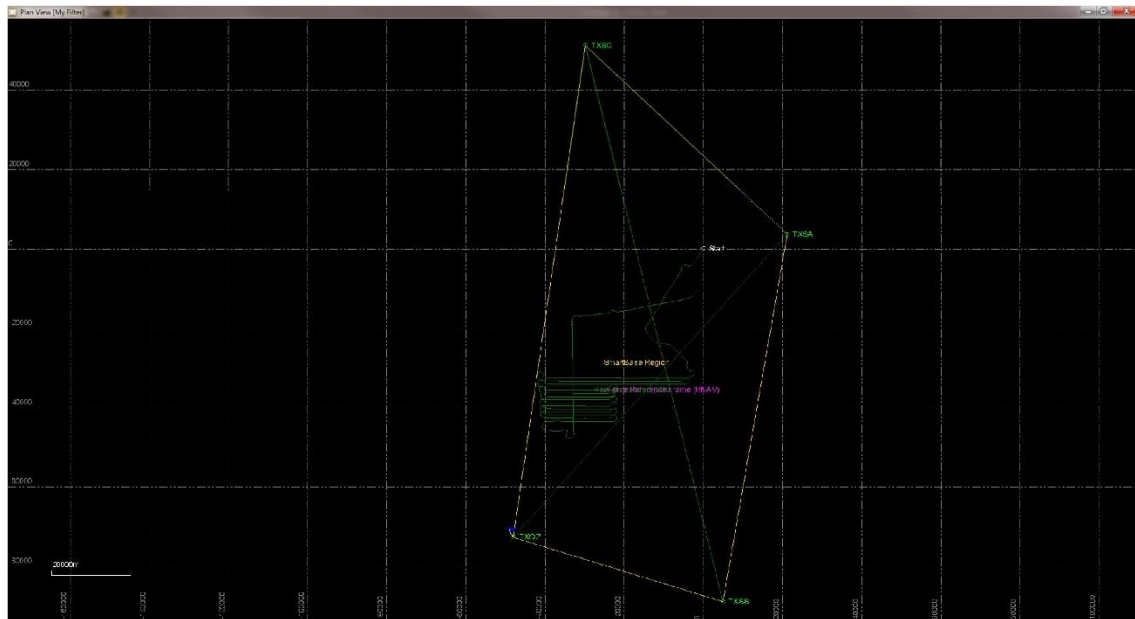


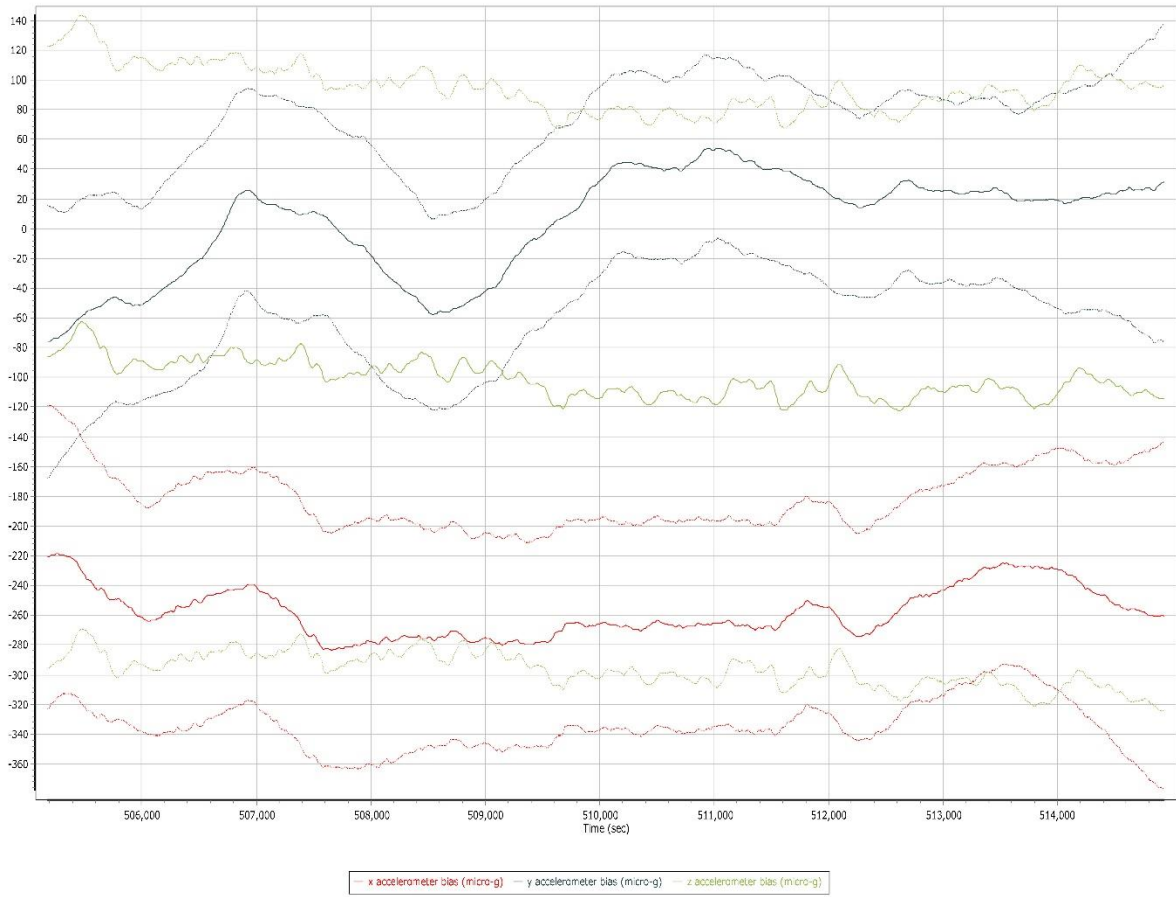
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IA PPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

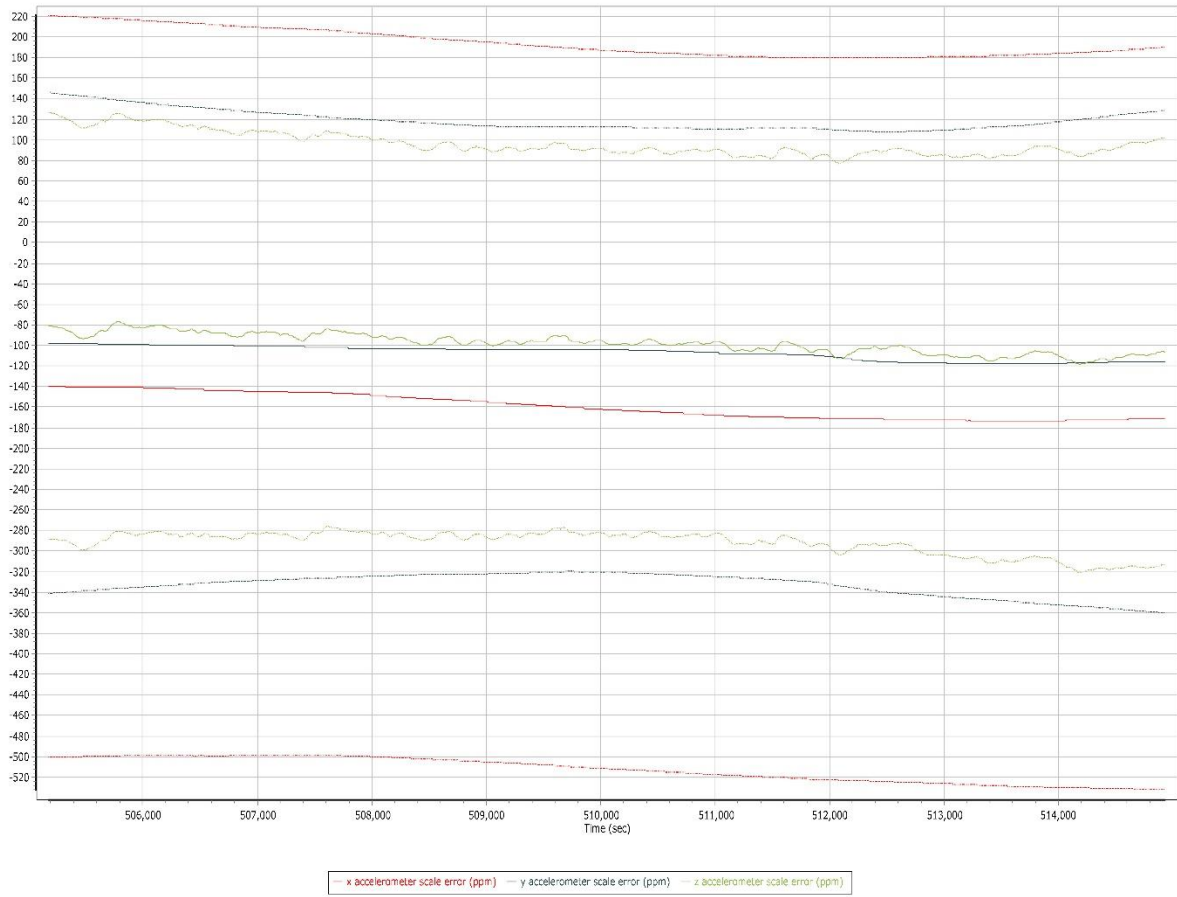


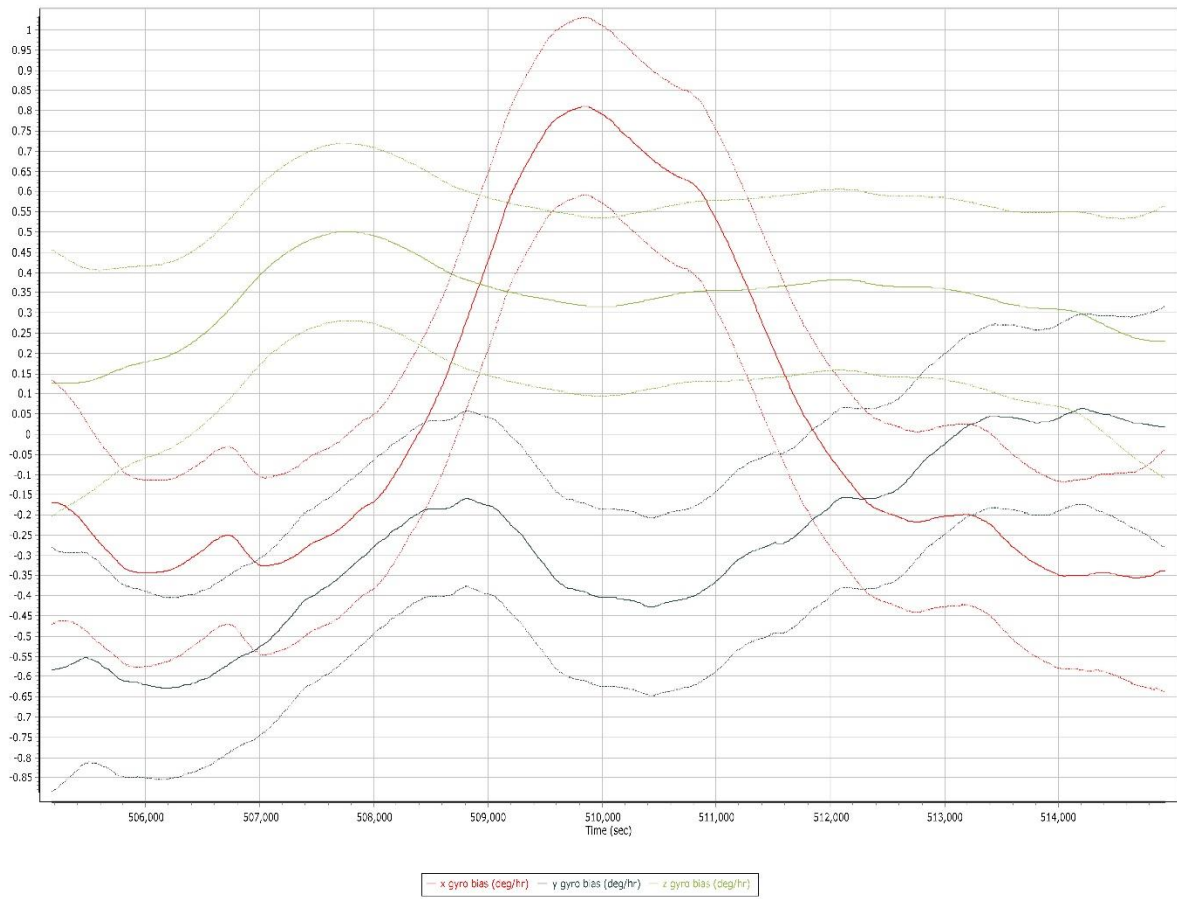


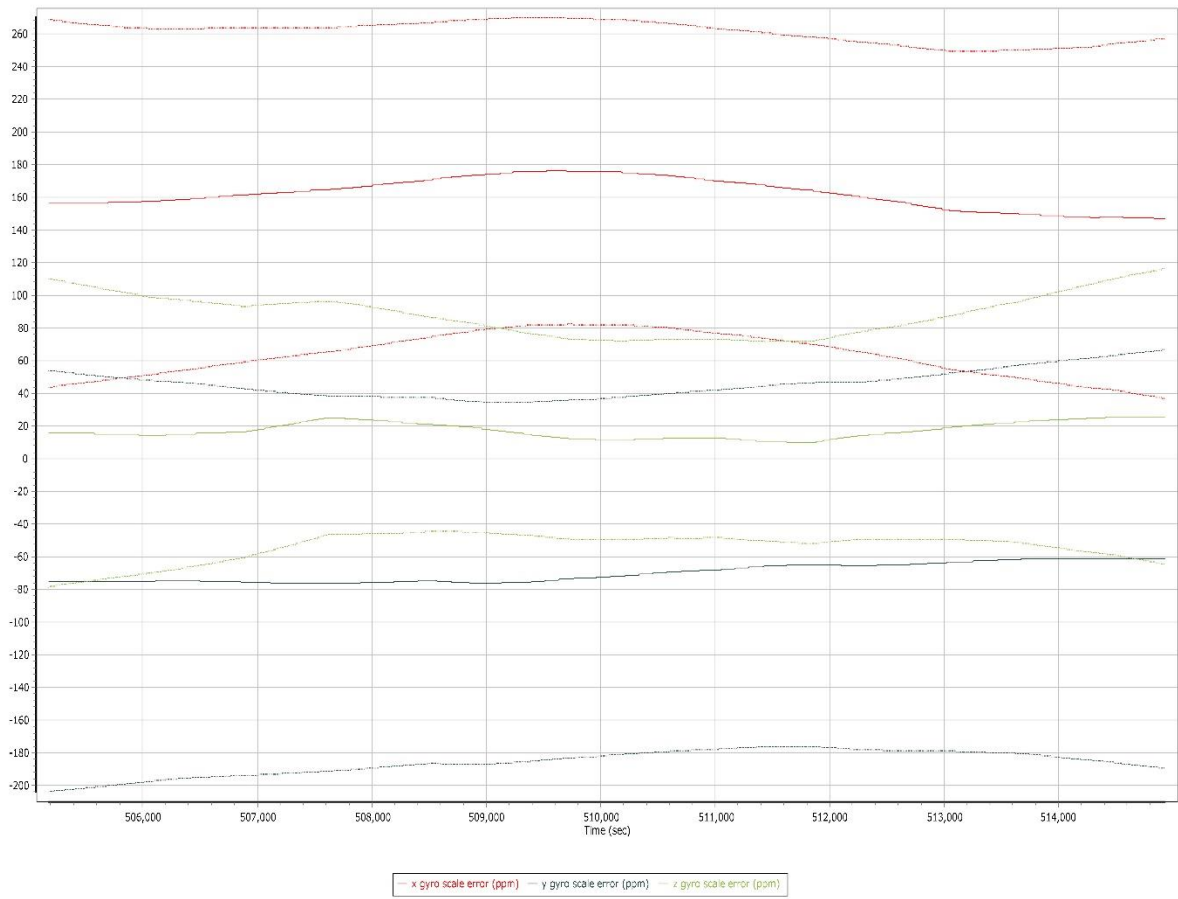




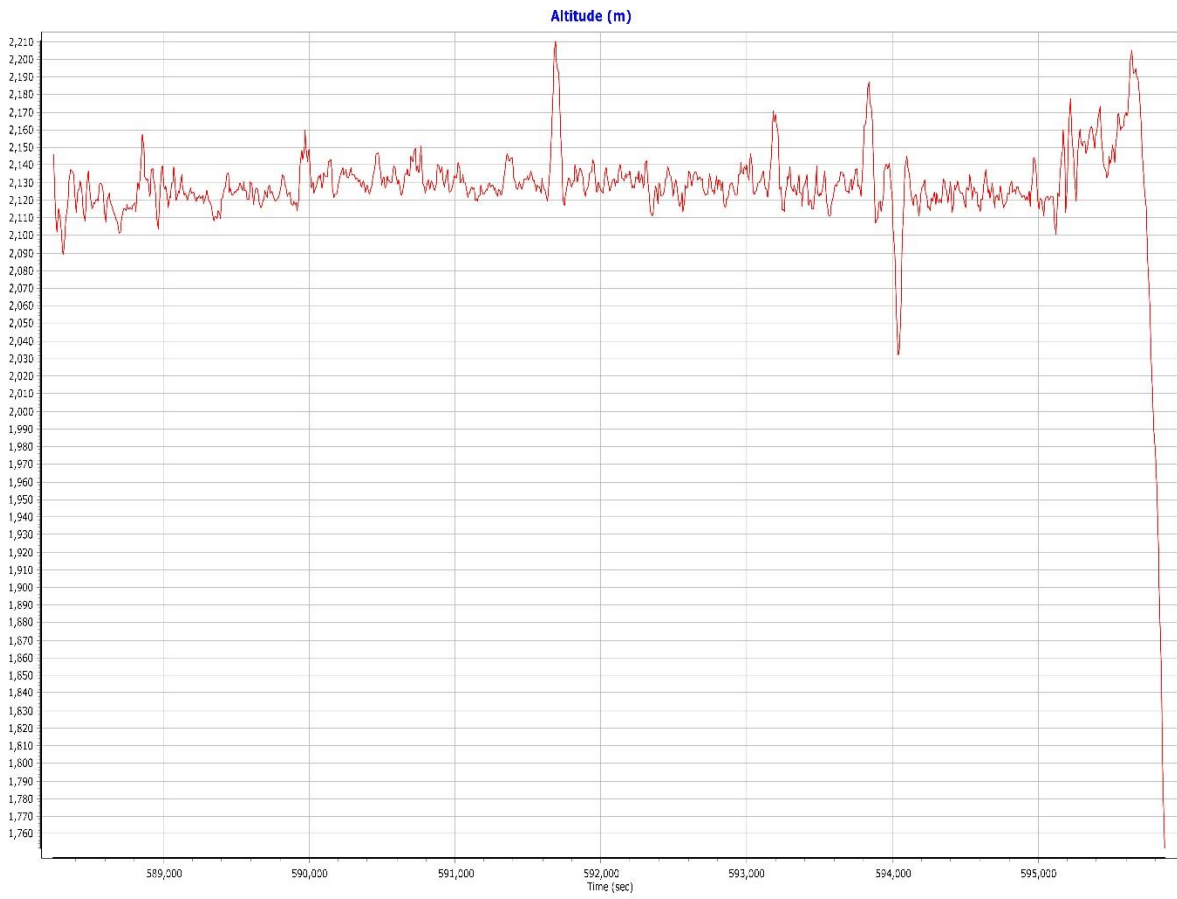


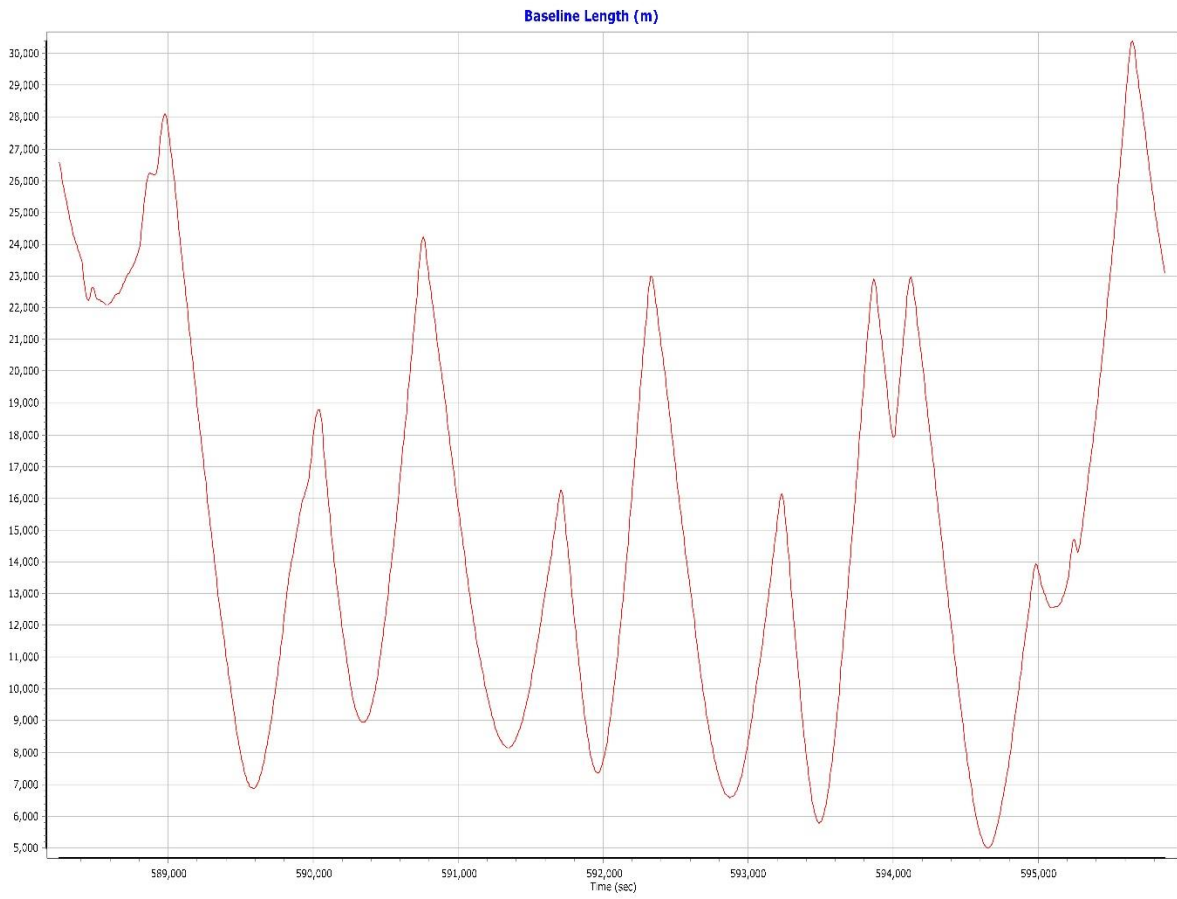


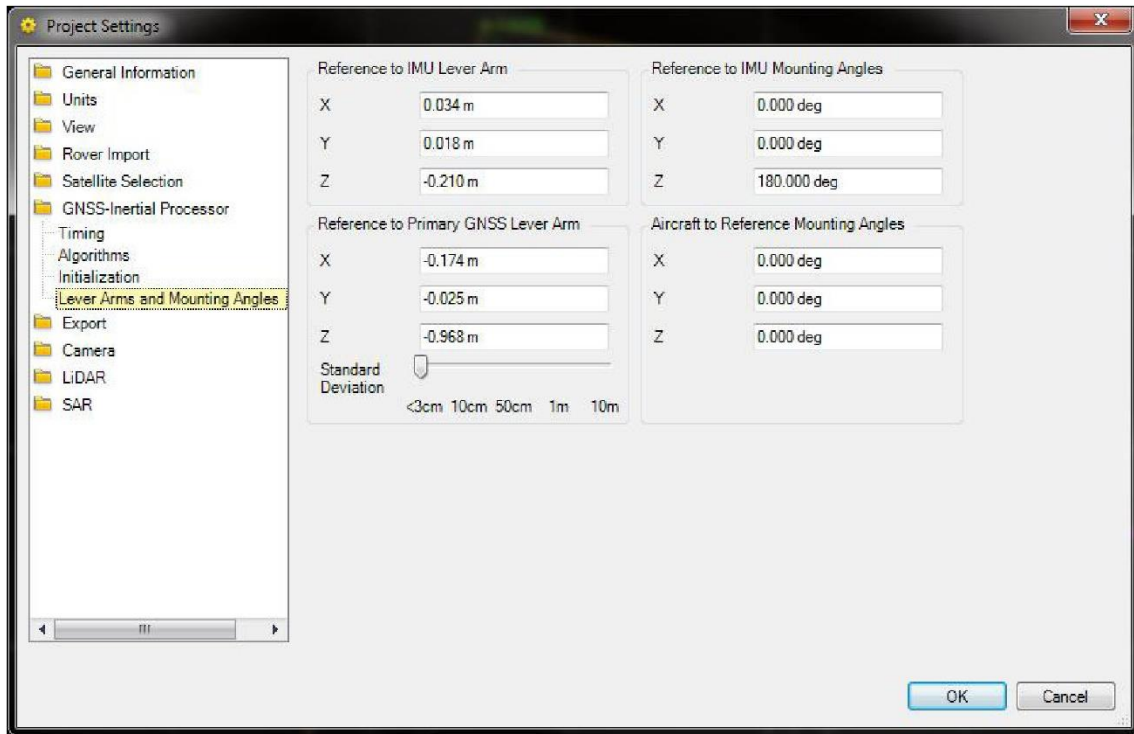


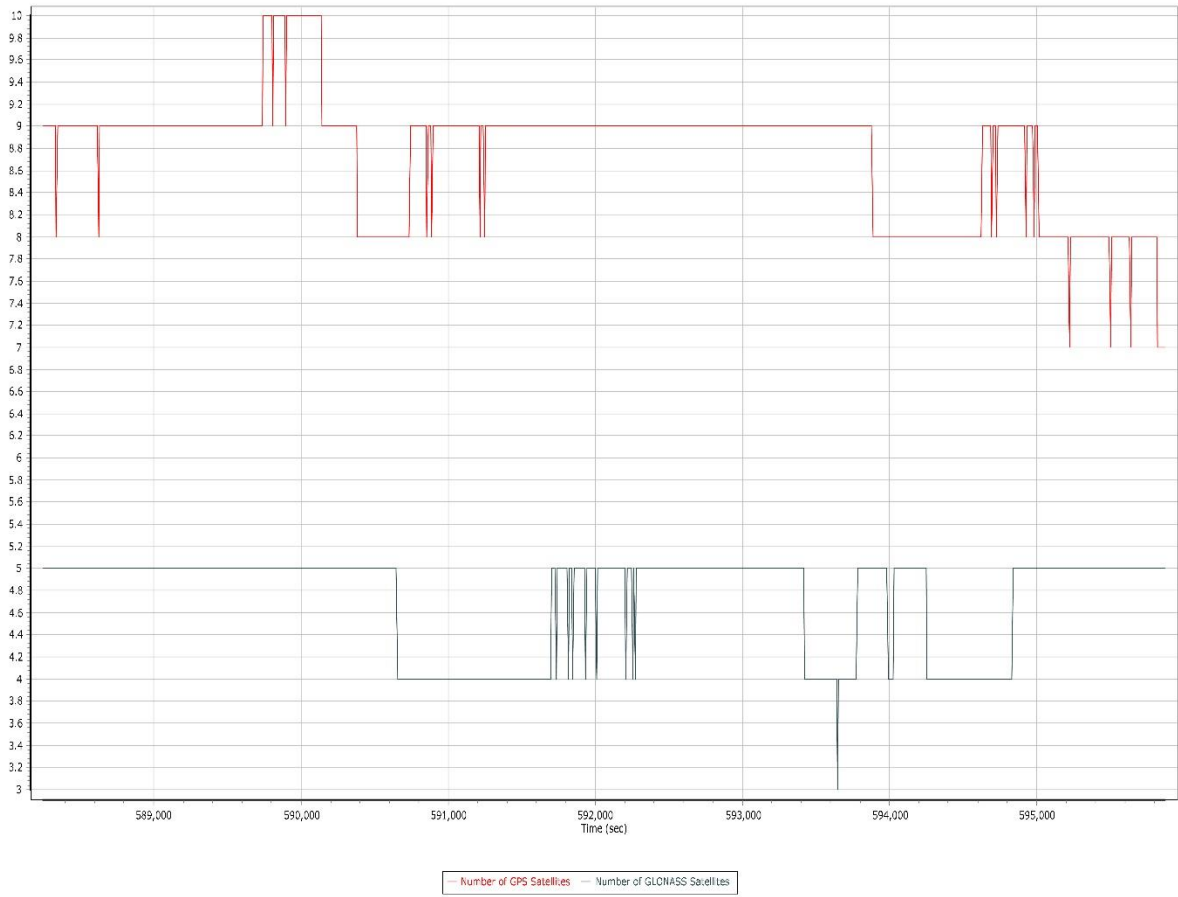


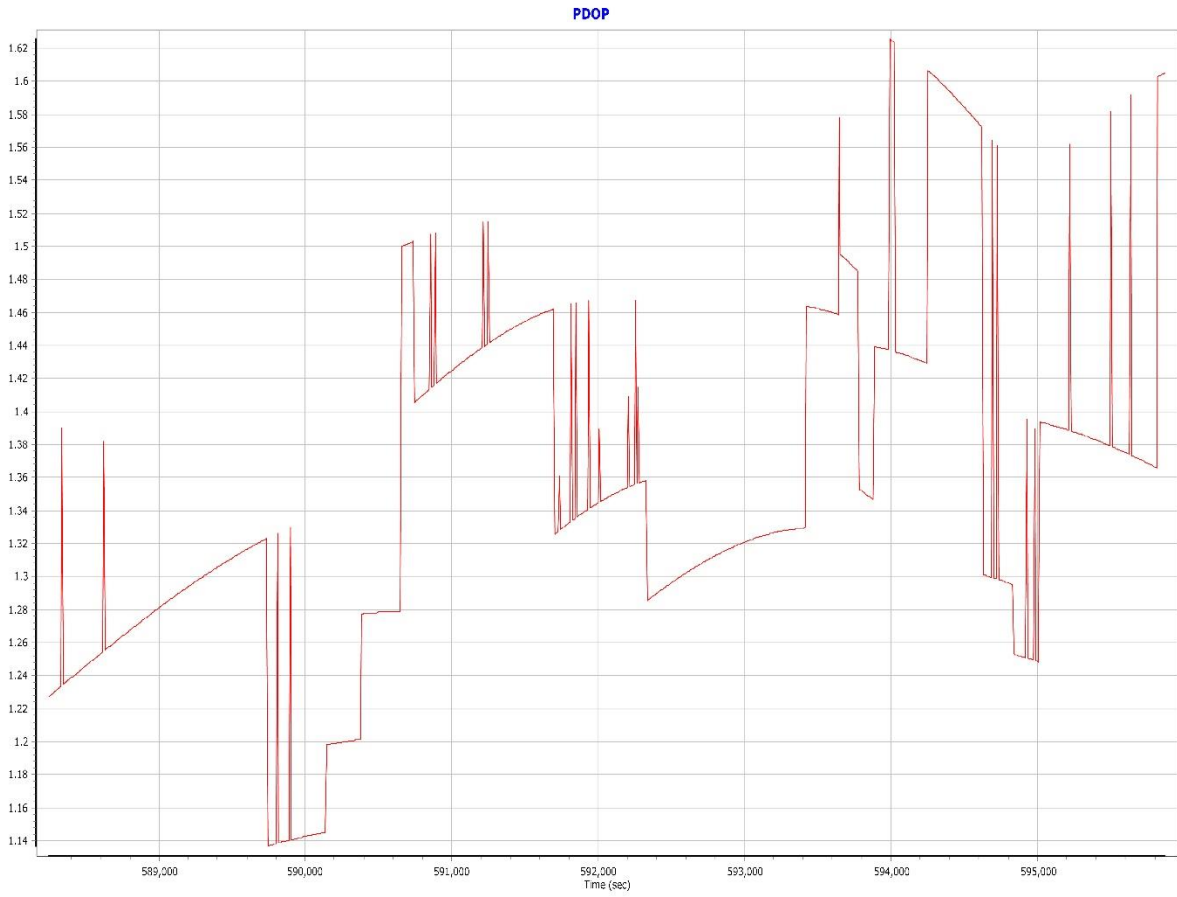
CAU18048A

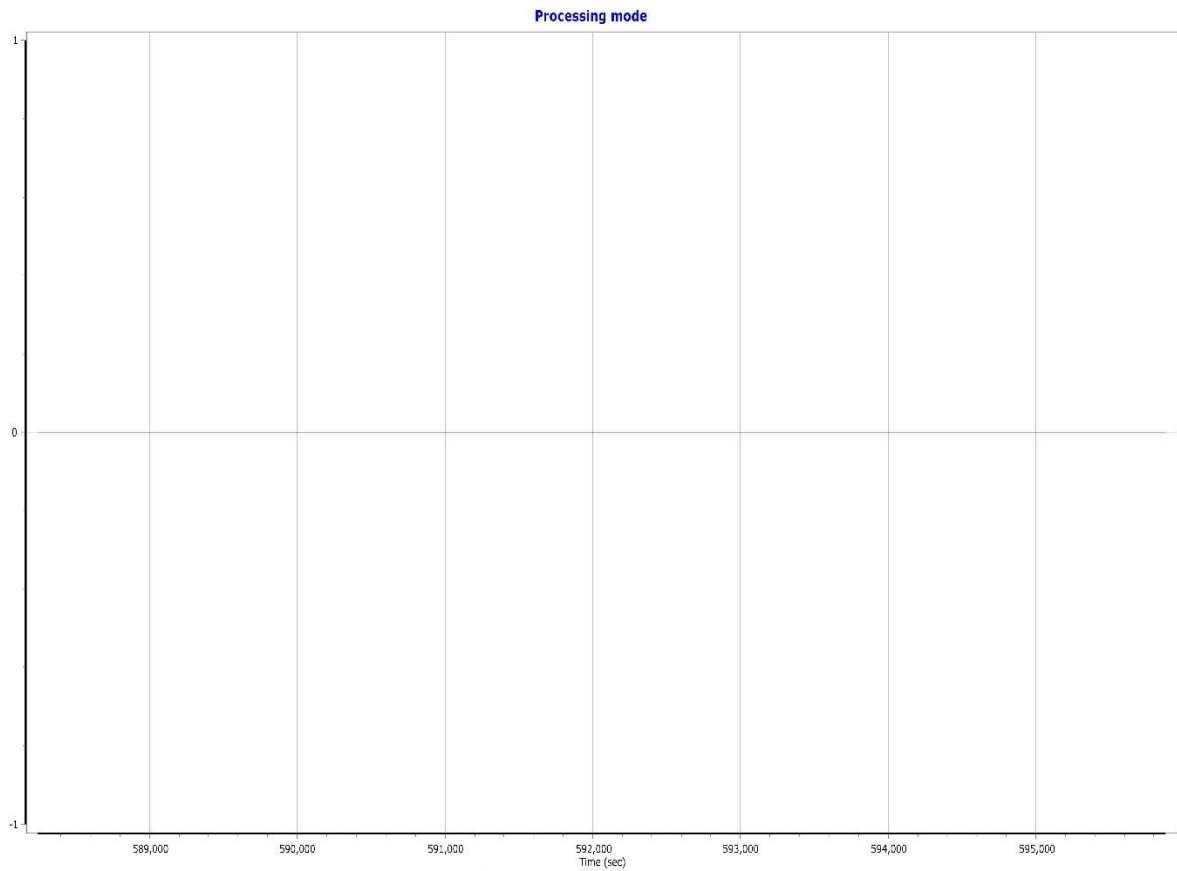






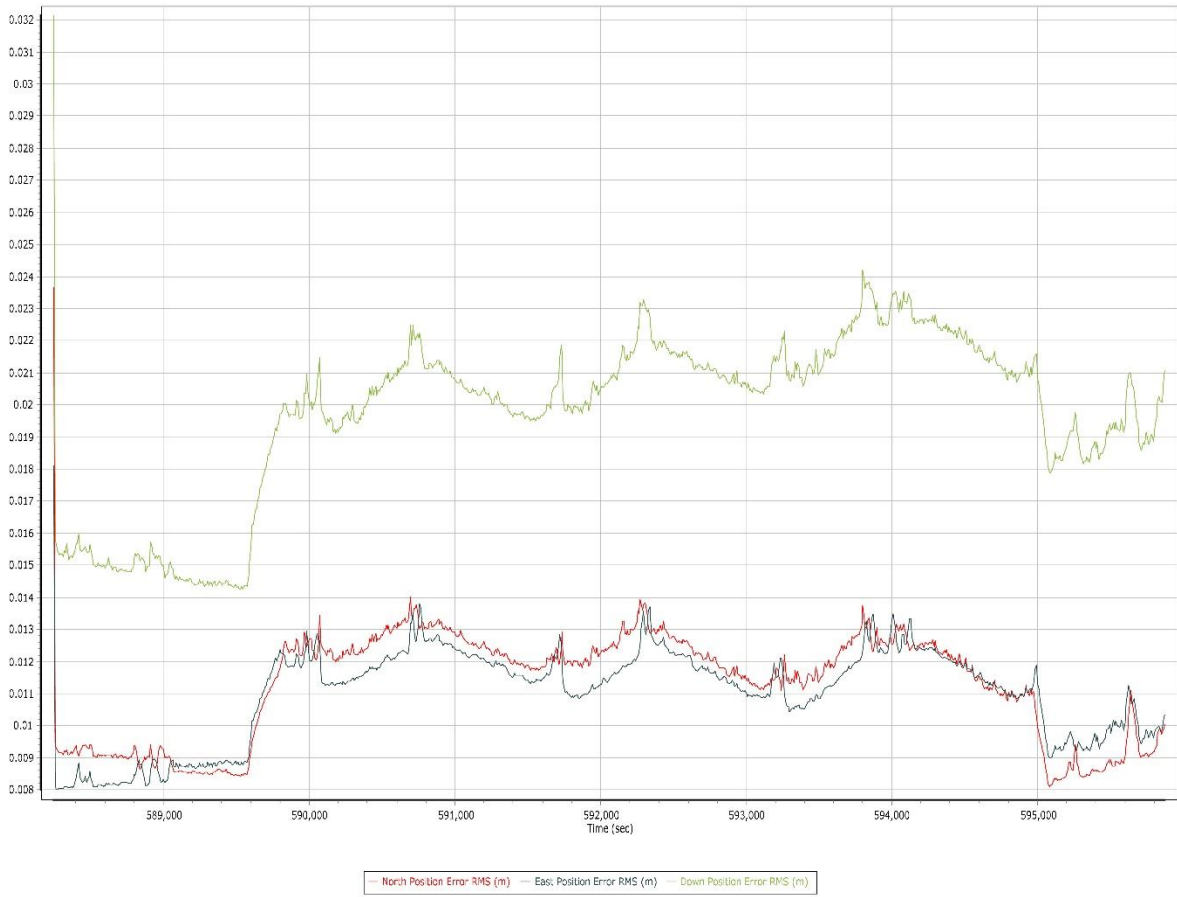


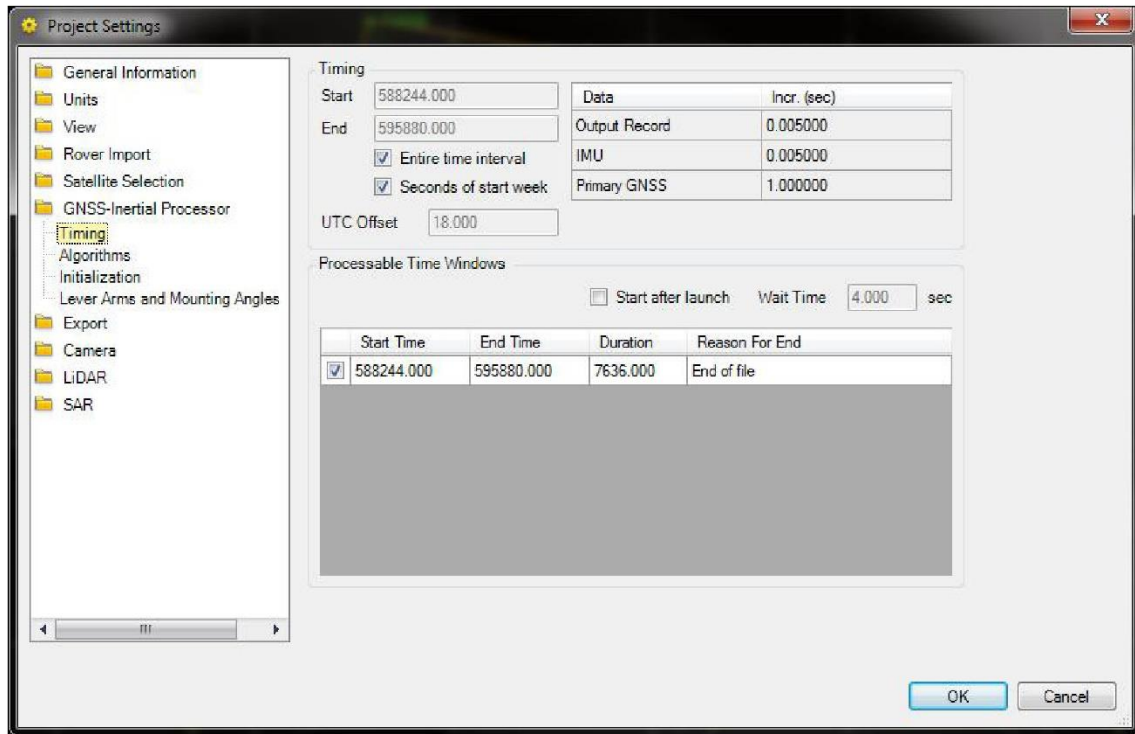


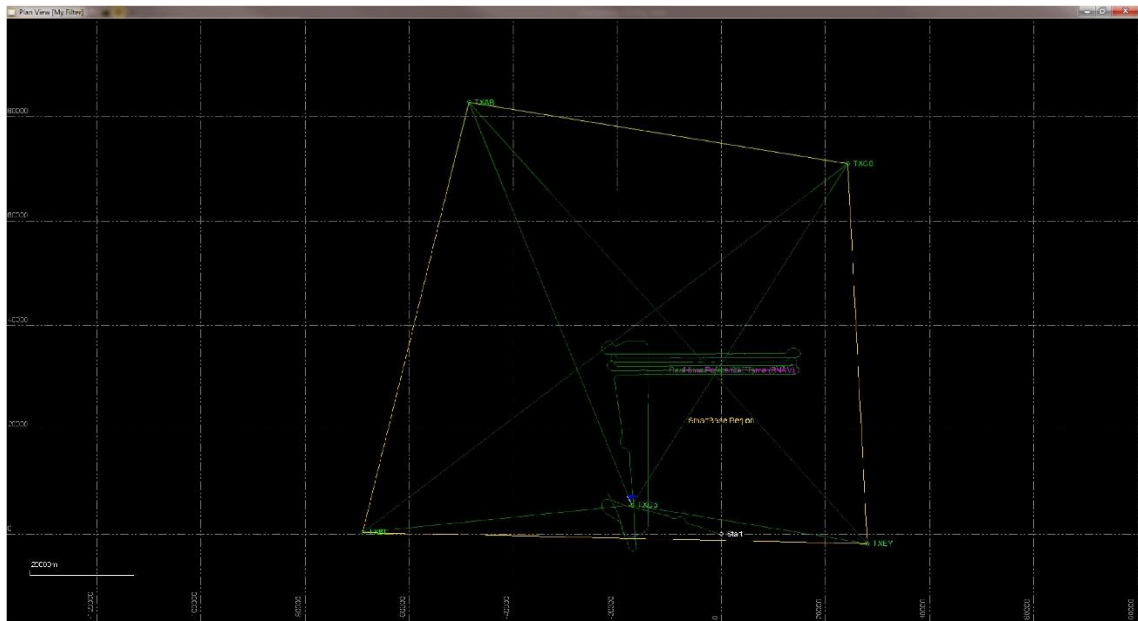


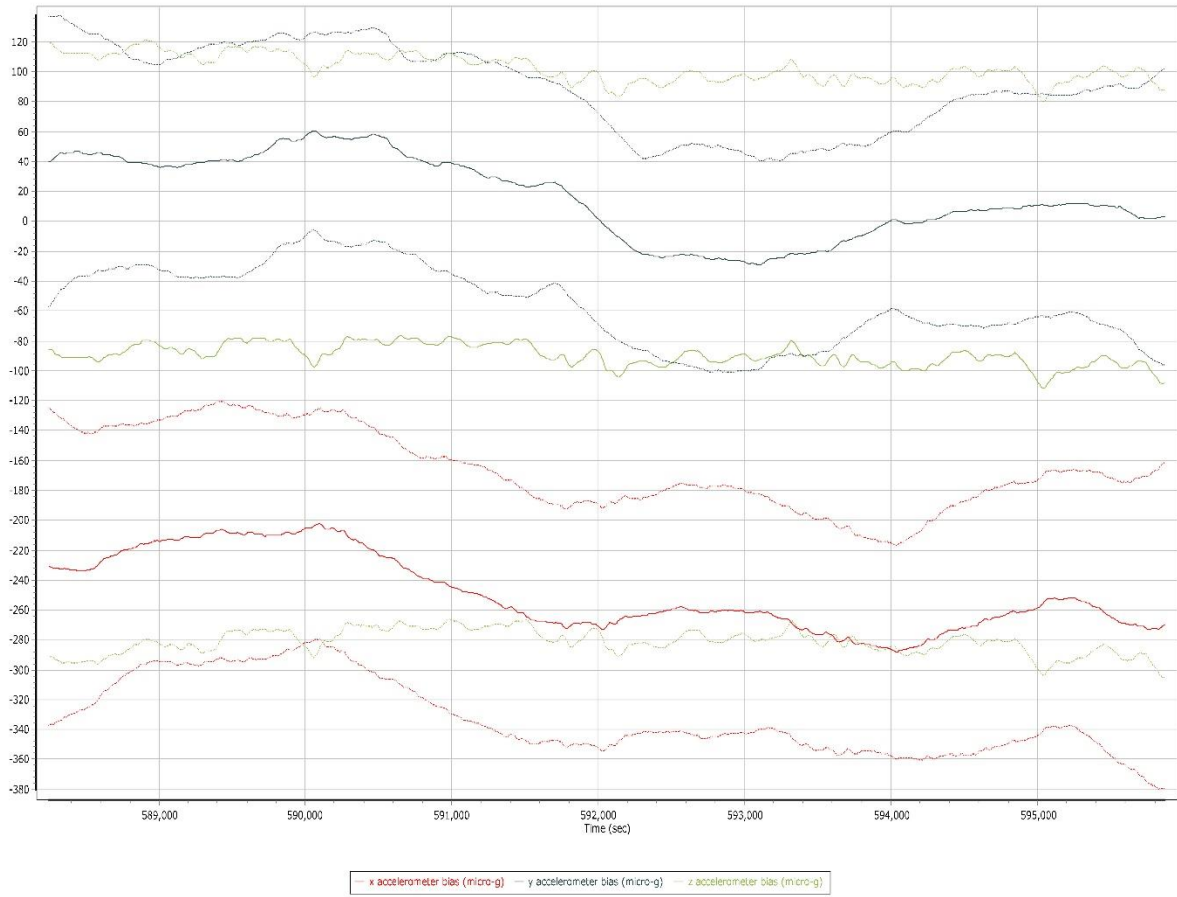
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IA*PPF, 6 = C/A, 7 = GNSS Nav, 8 = DR

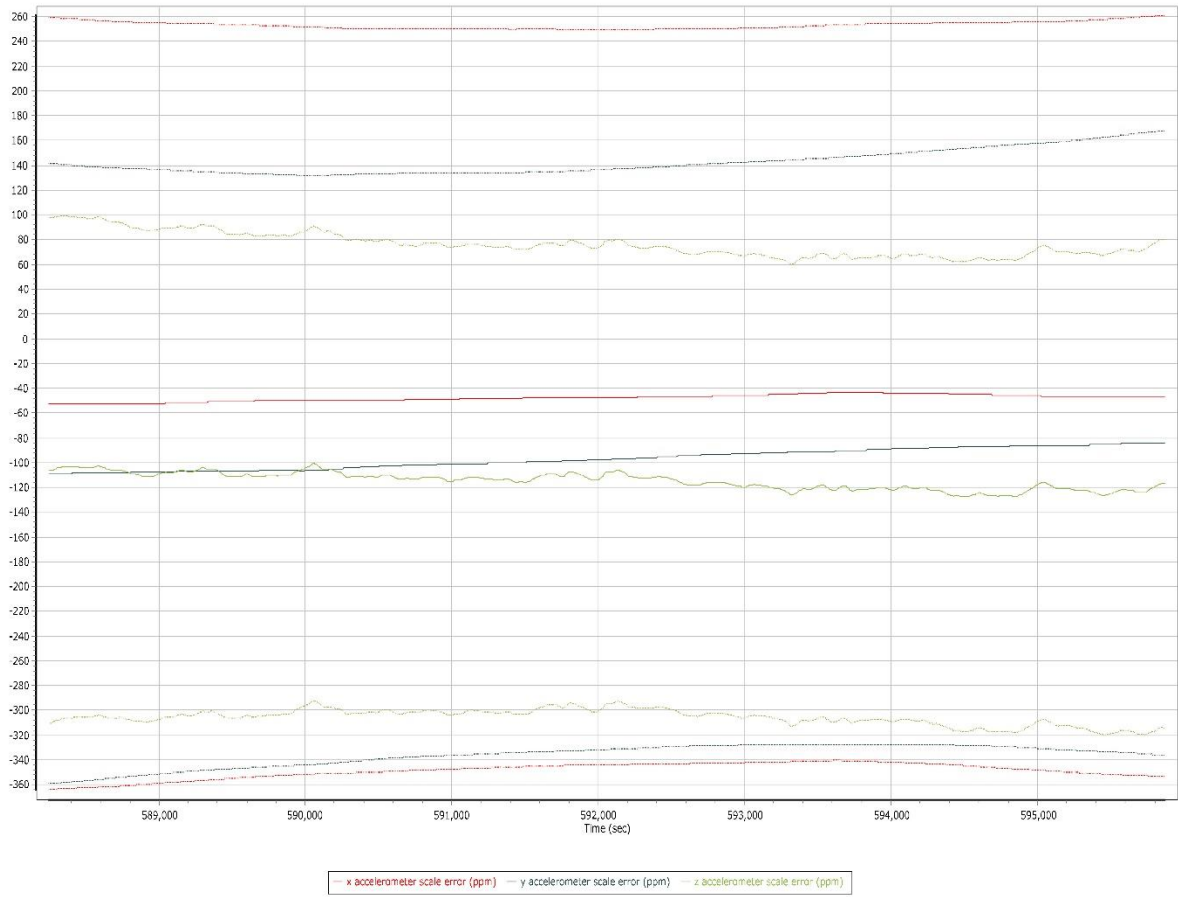


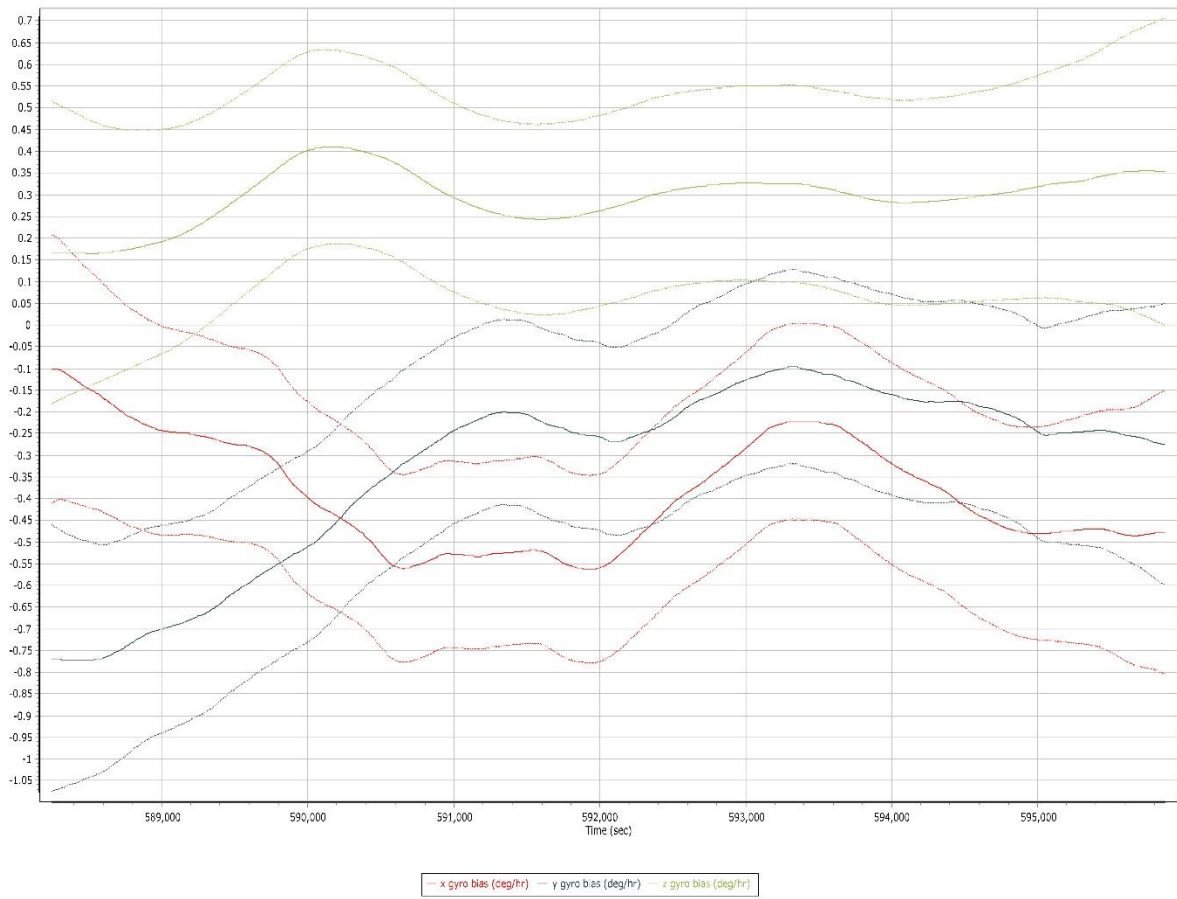


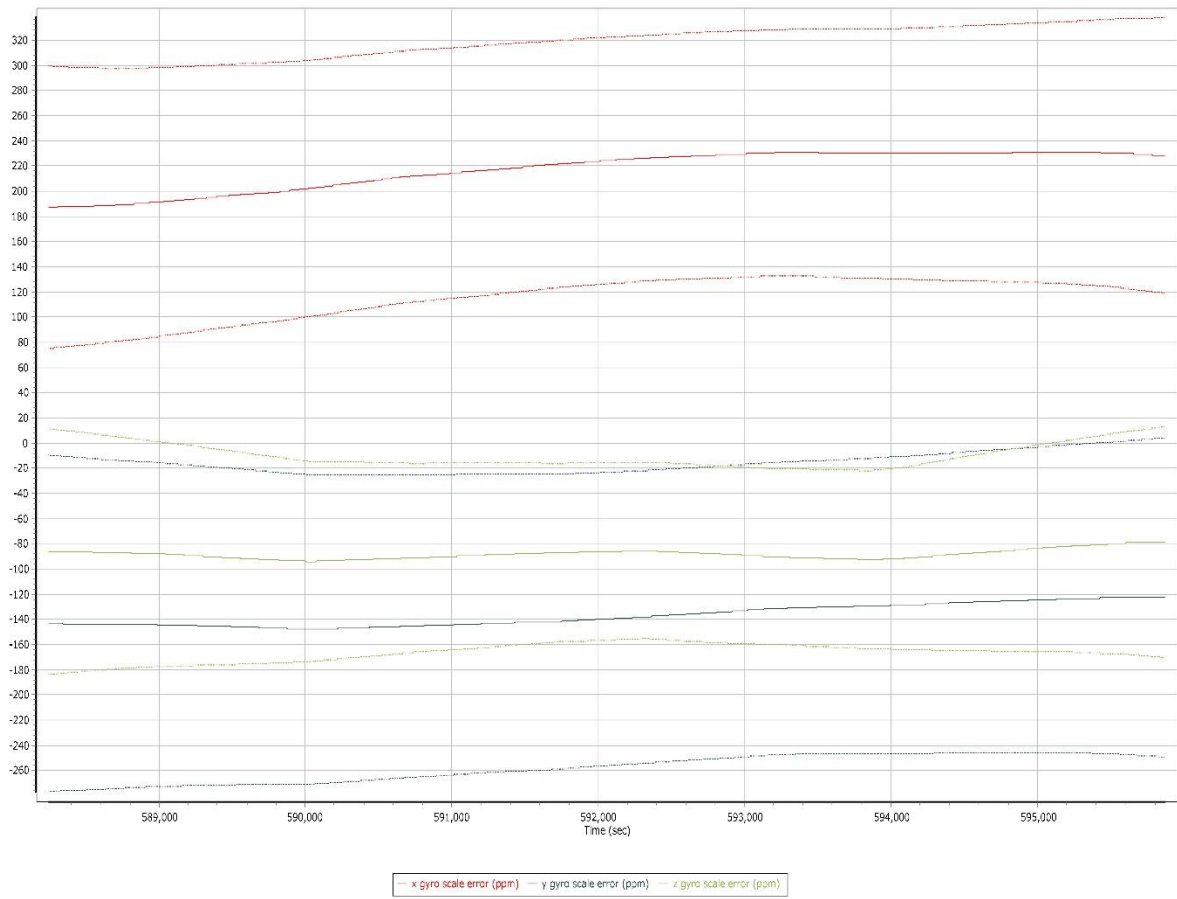




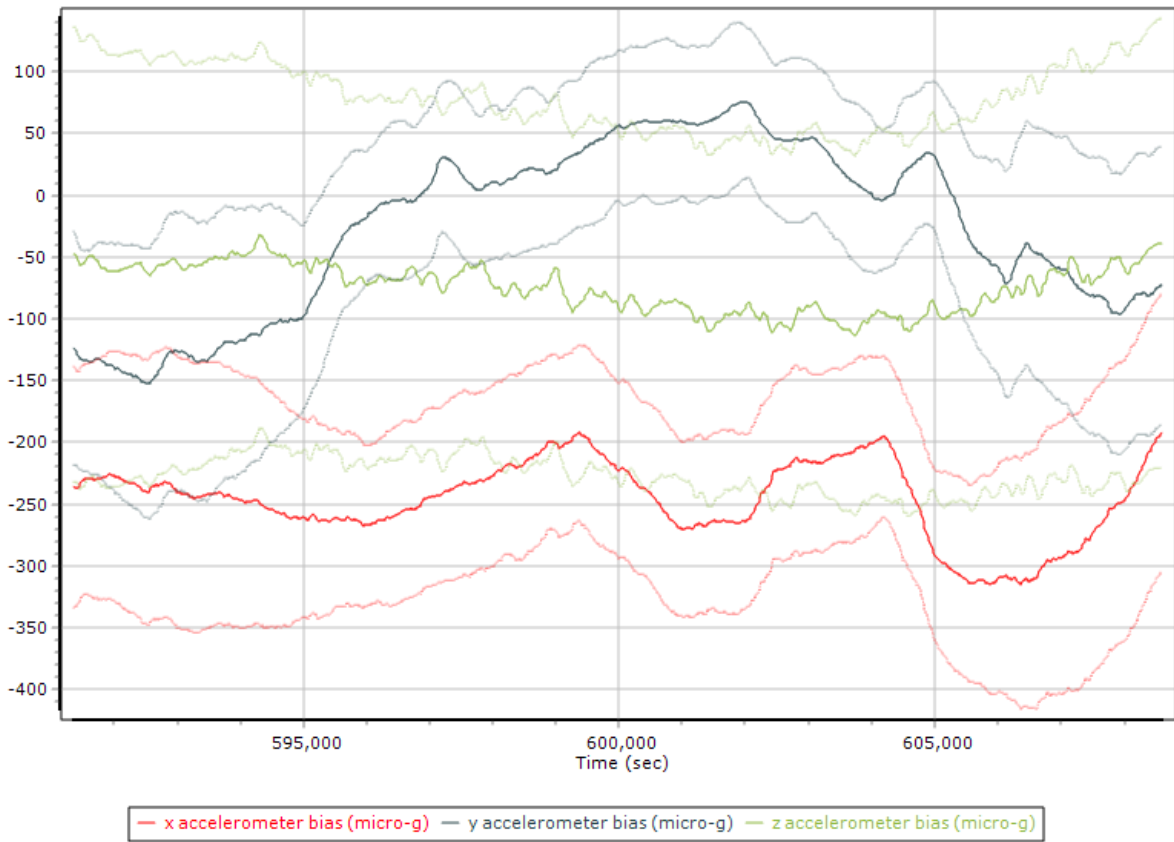


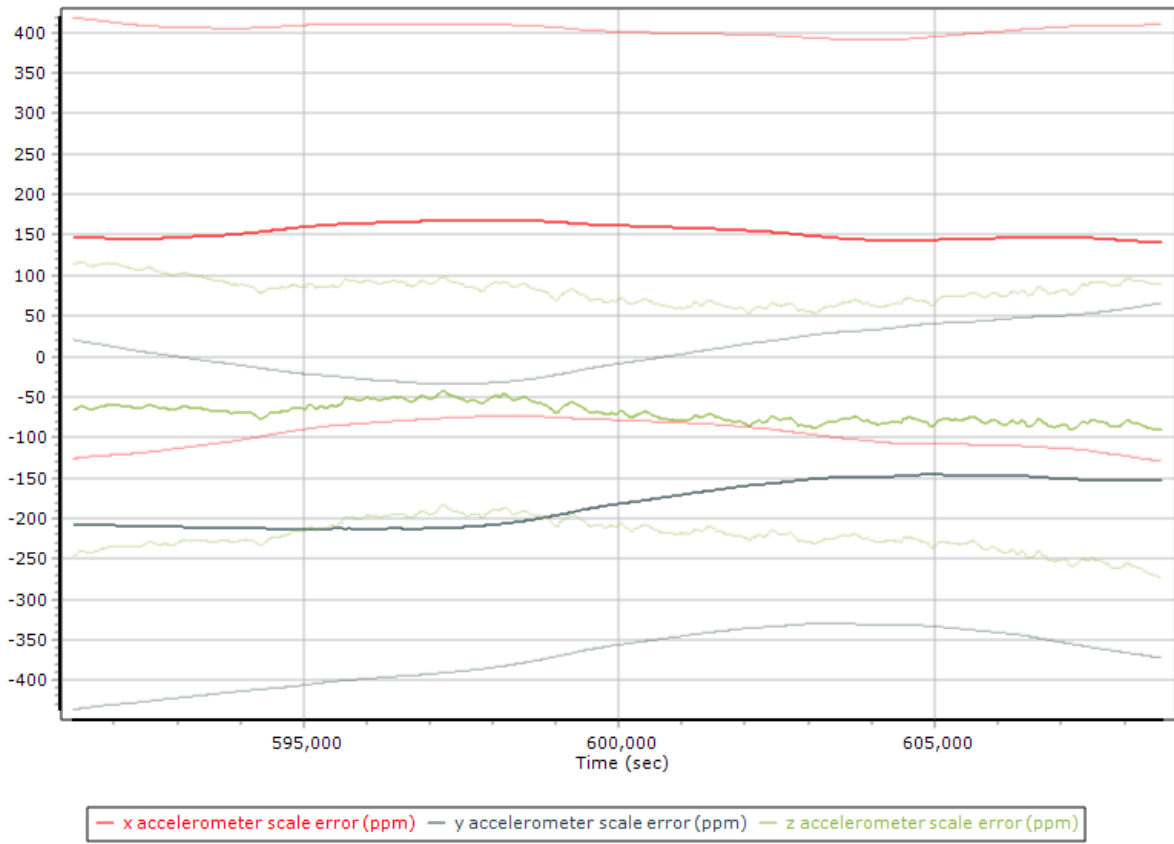


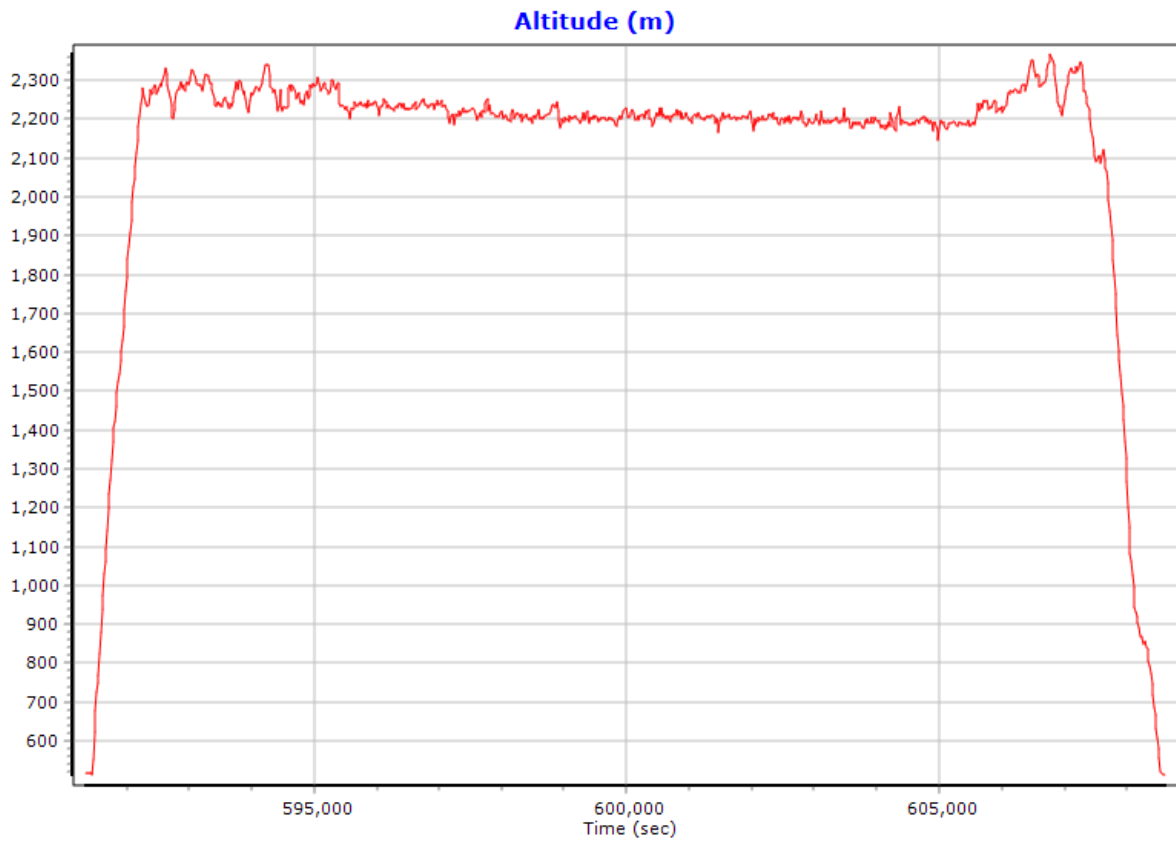


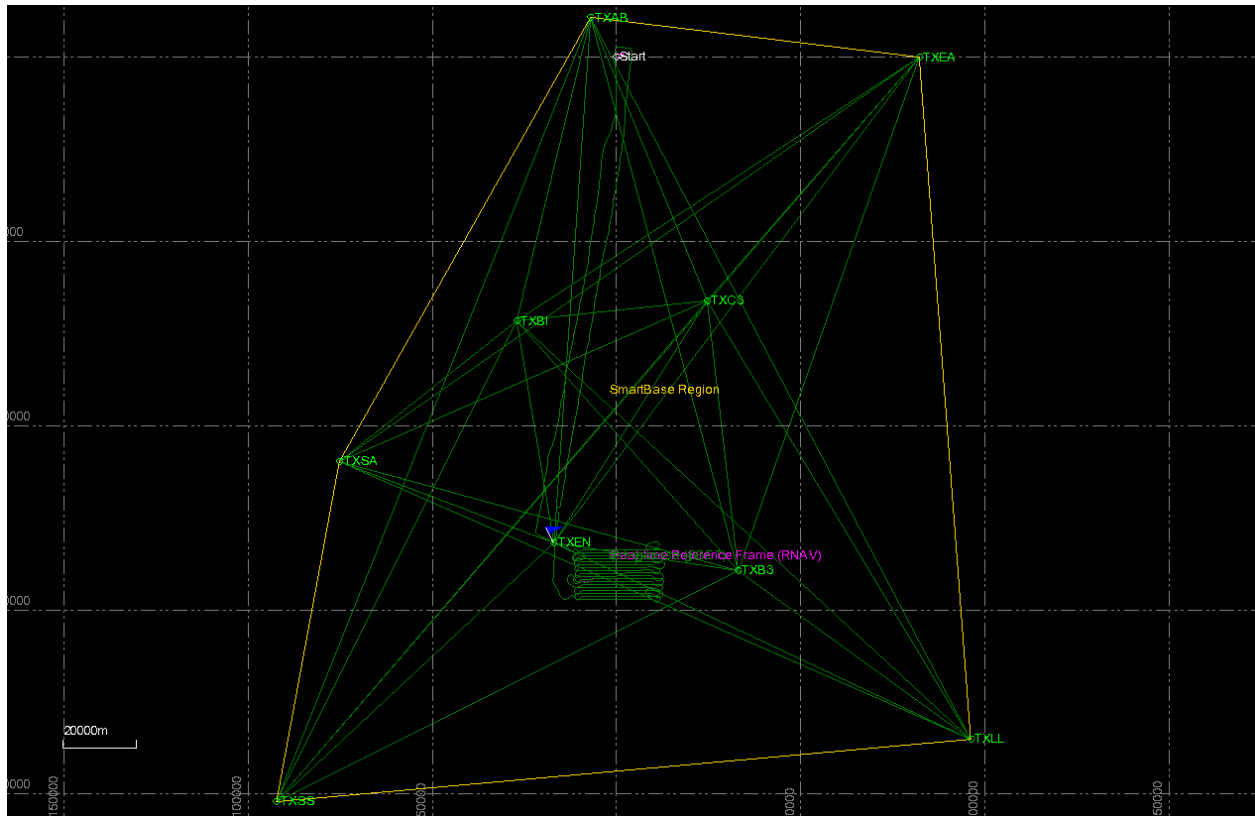
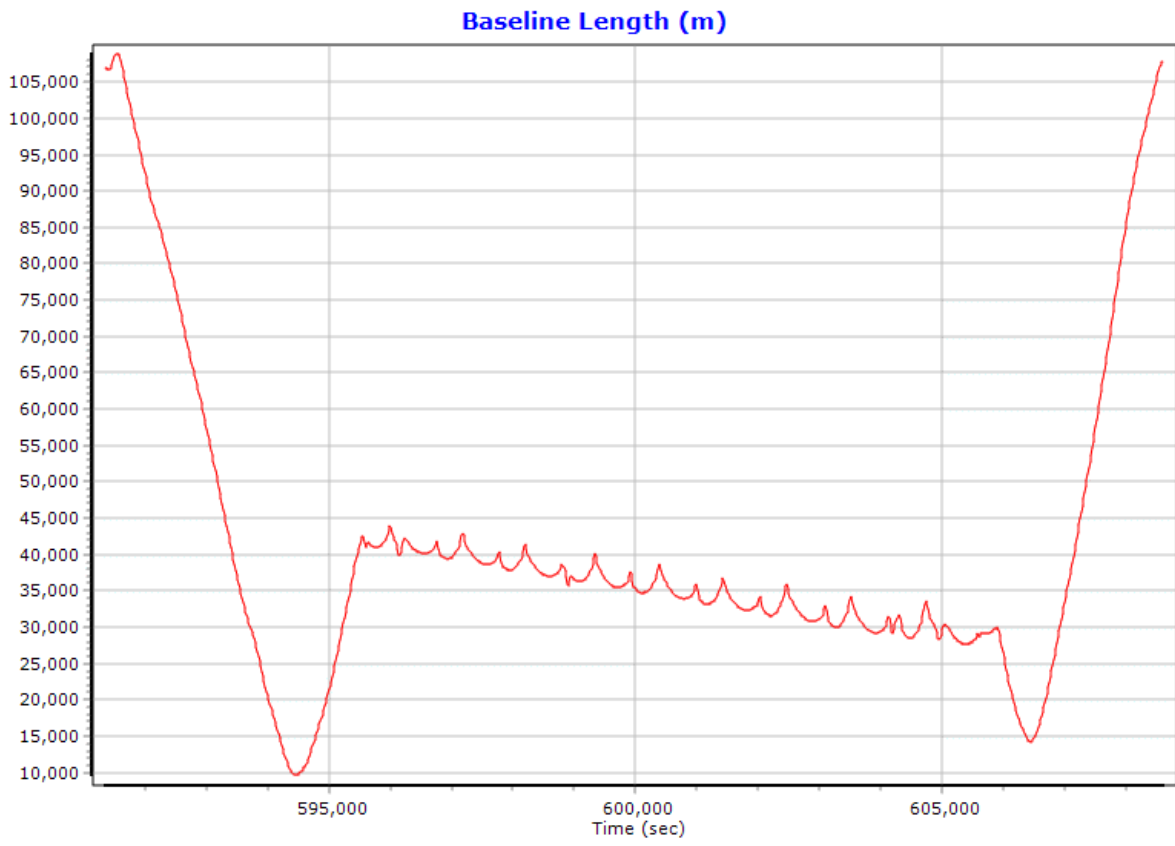


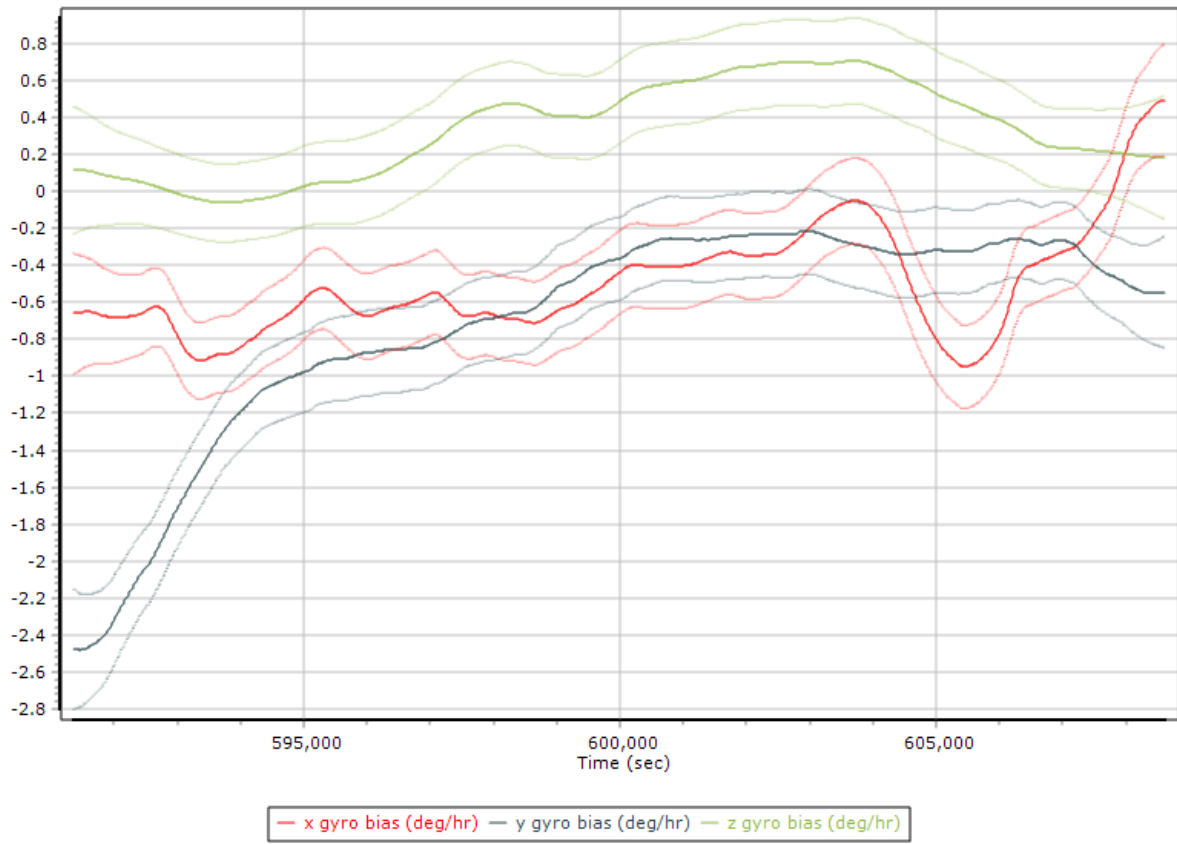
CAU18055A

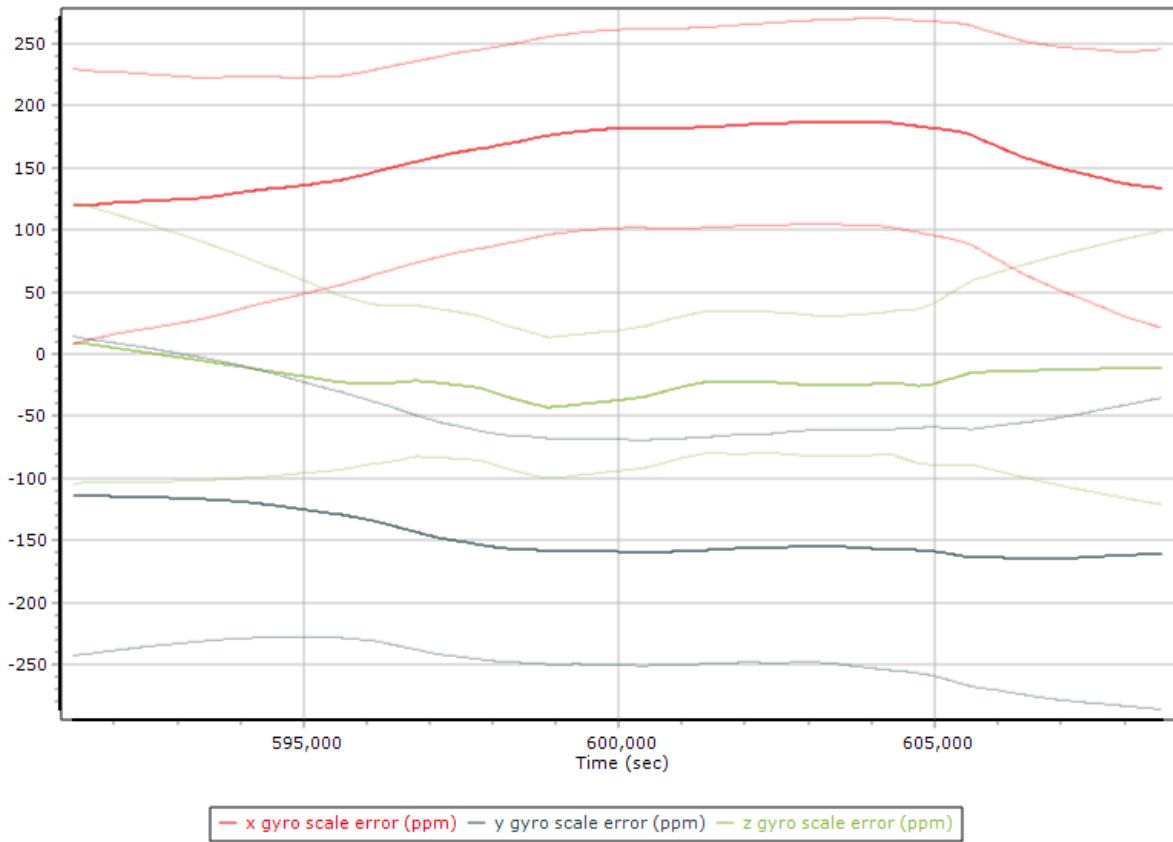












Project Settings [Close]

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation: (Selected)

<3cm 10cm 50cm 1m 10m

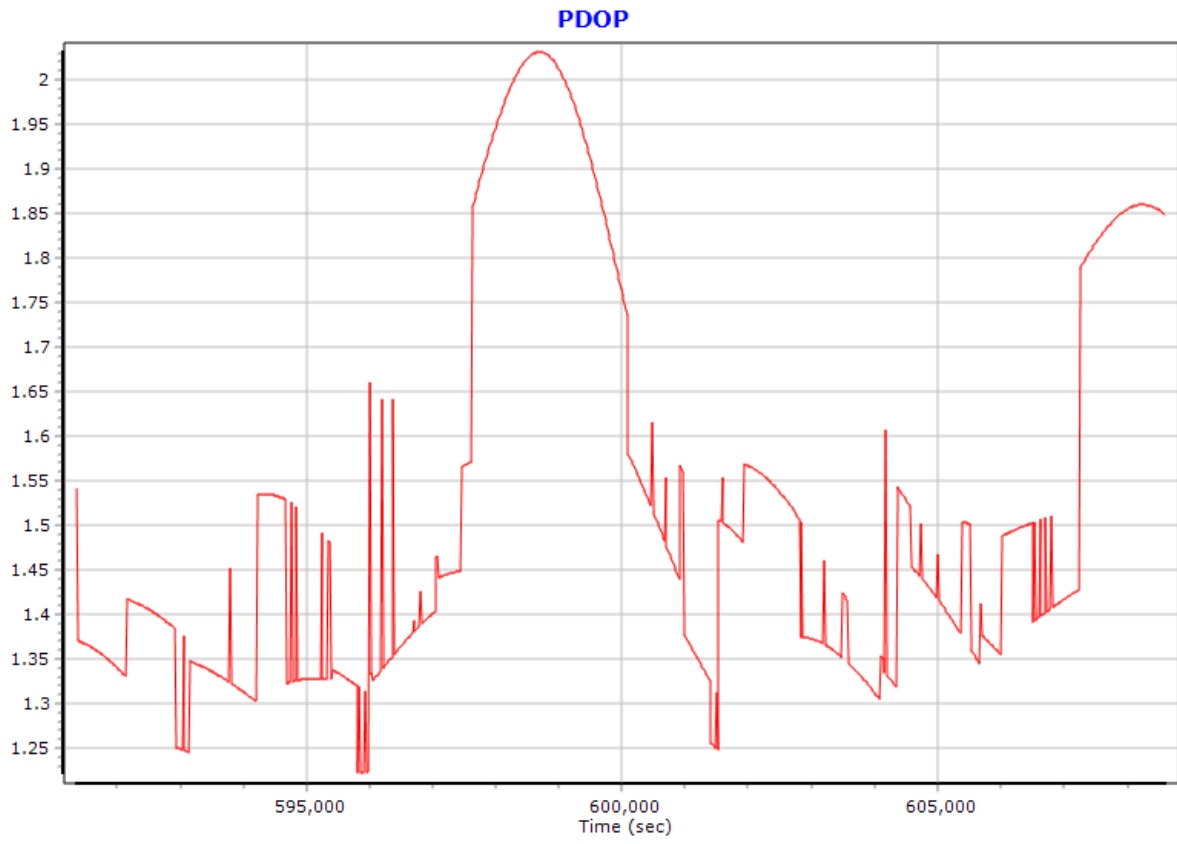
Aircraft to Reference Mounting Angles

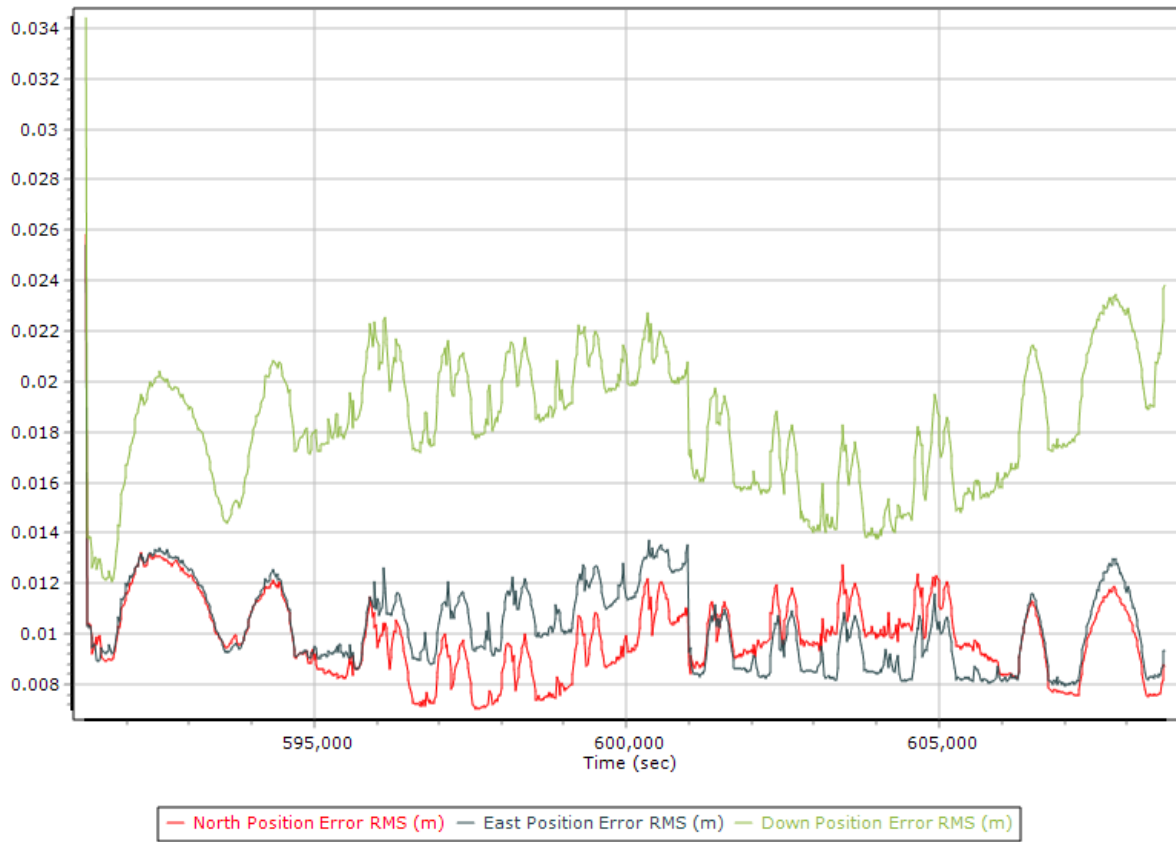
X:

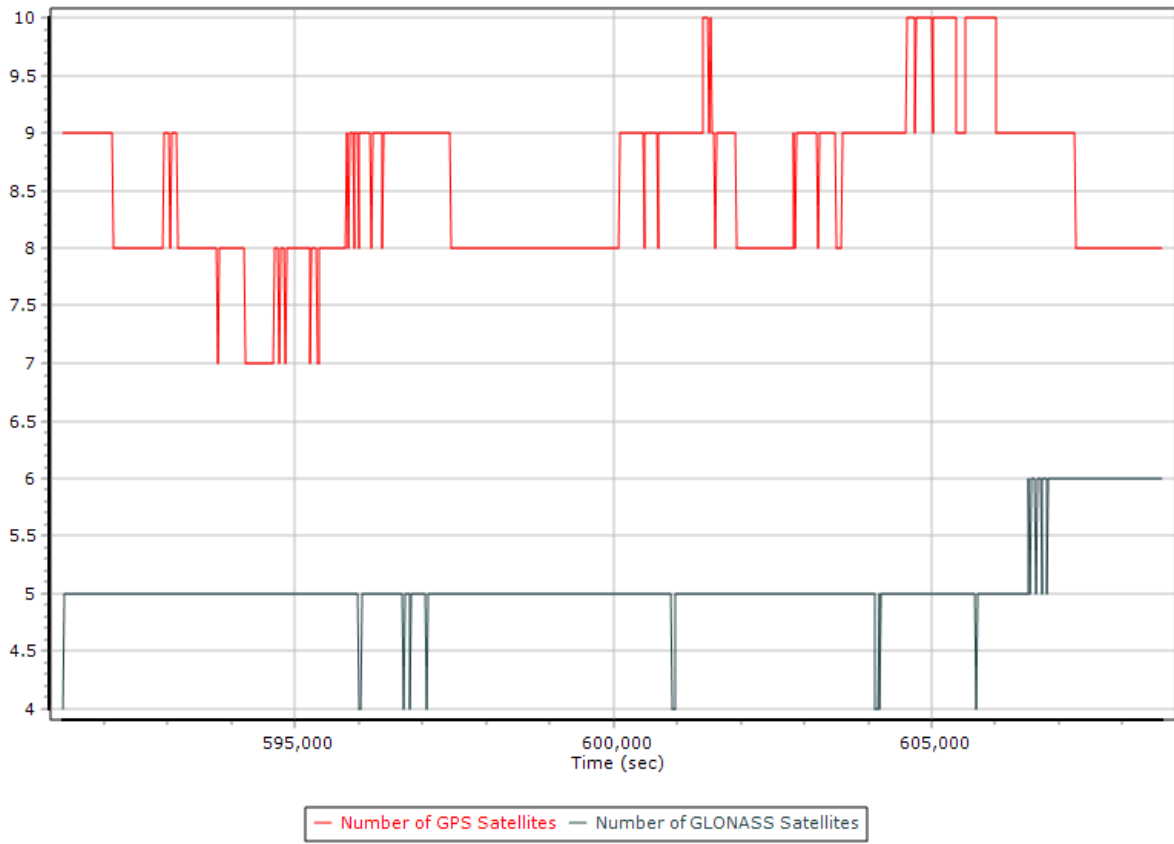
Y:

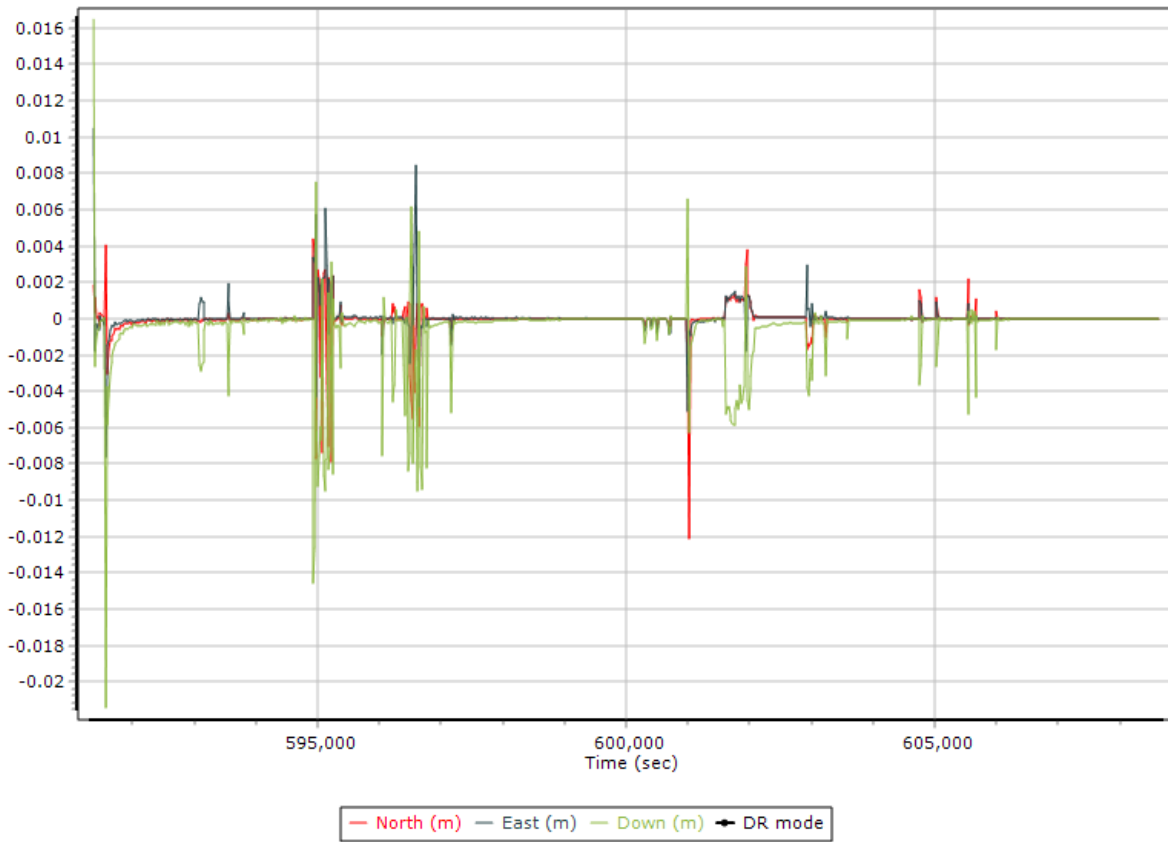
Z:

[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: 590781.000
End: 608644.000

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

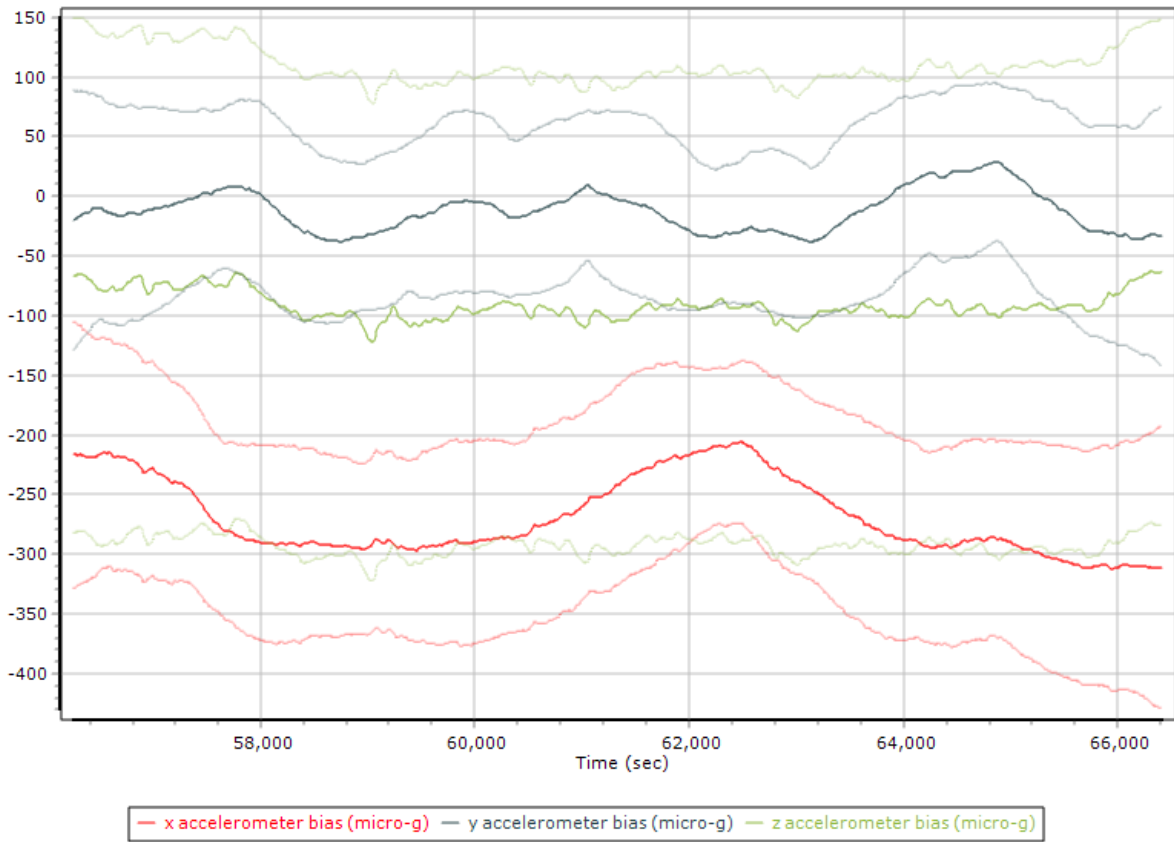
Processable Time Windows

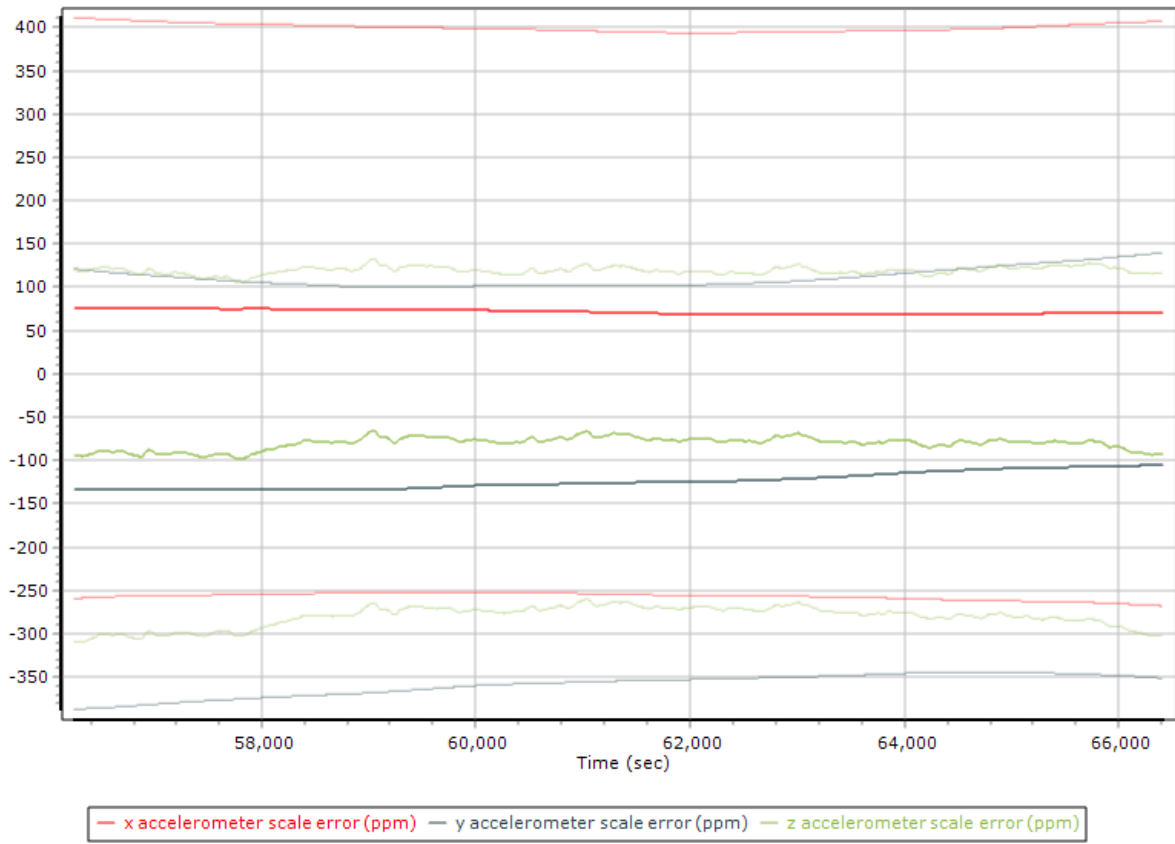
Start after launch Wait Time: 4.000 sec

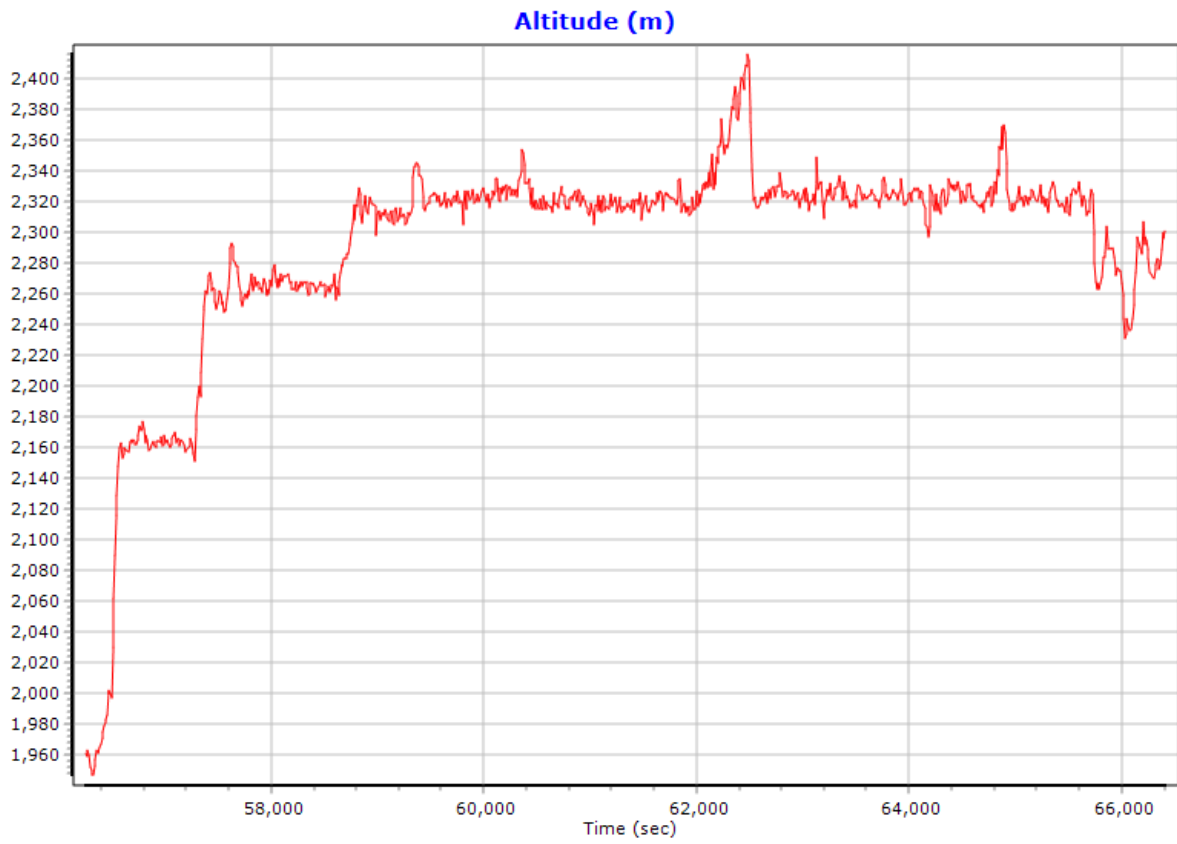
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	590781.000	608644.000	17863.000	End of file

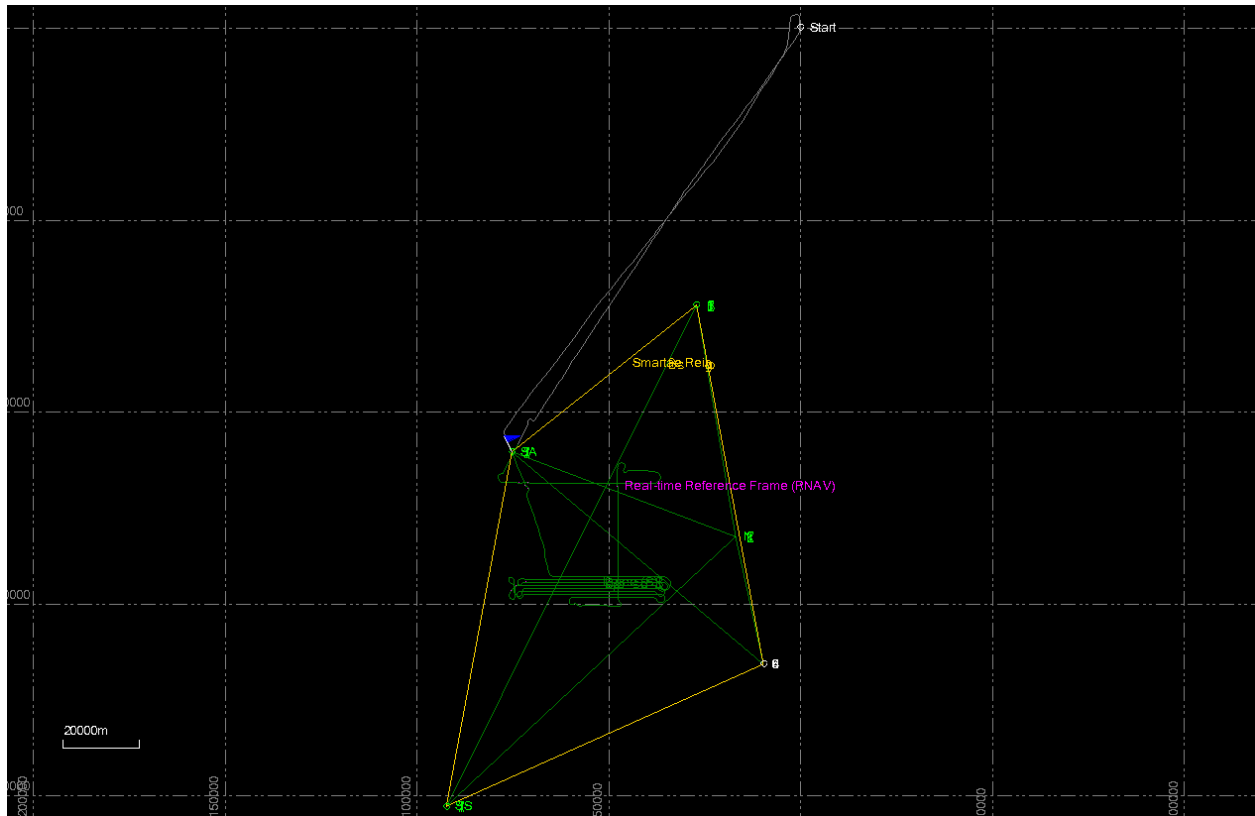
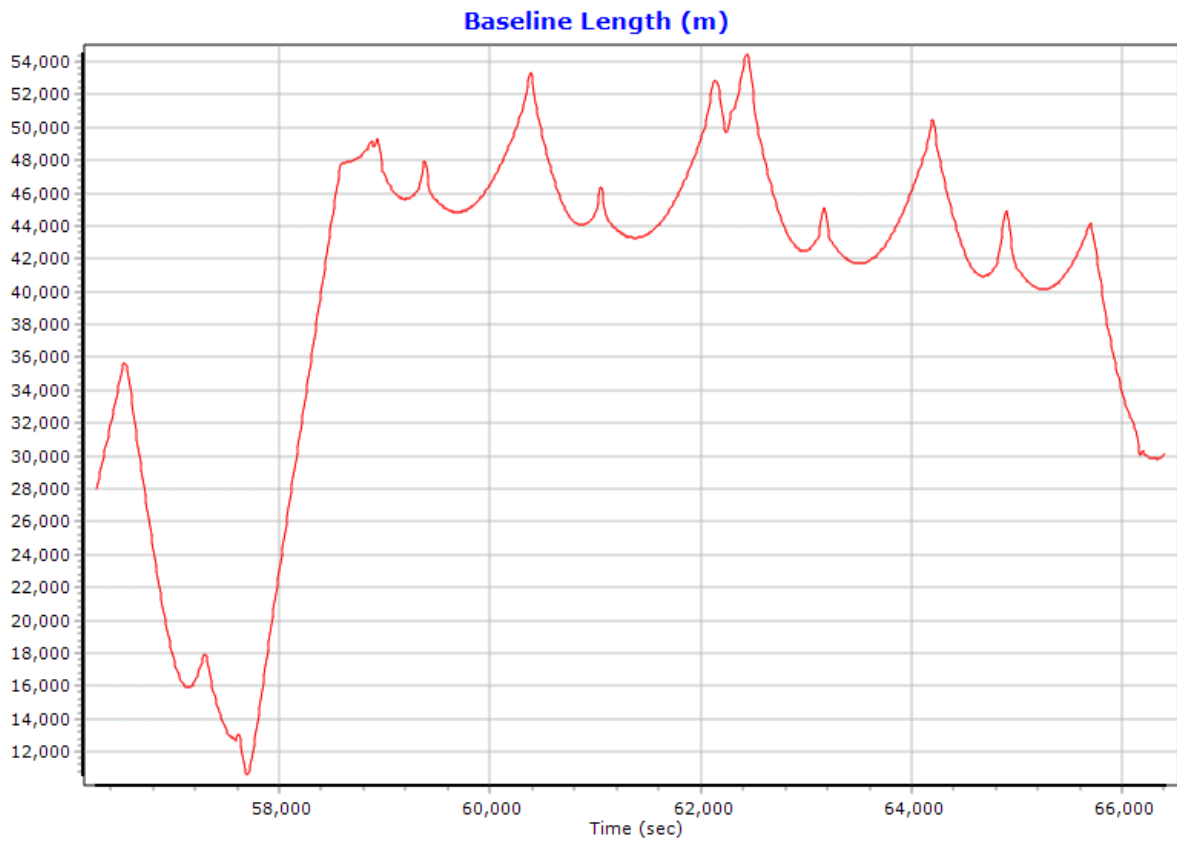
OK Cancel

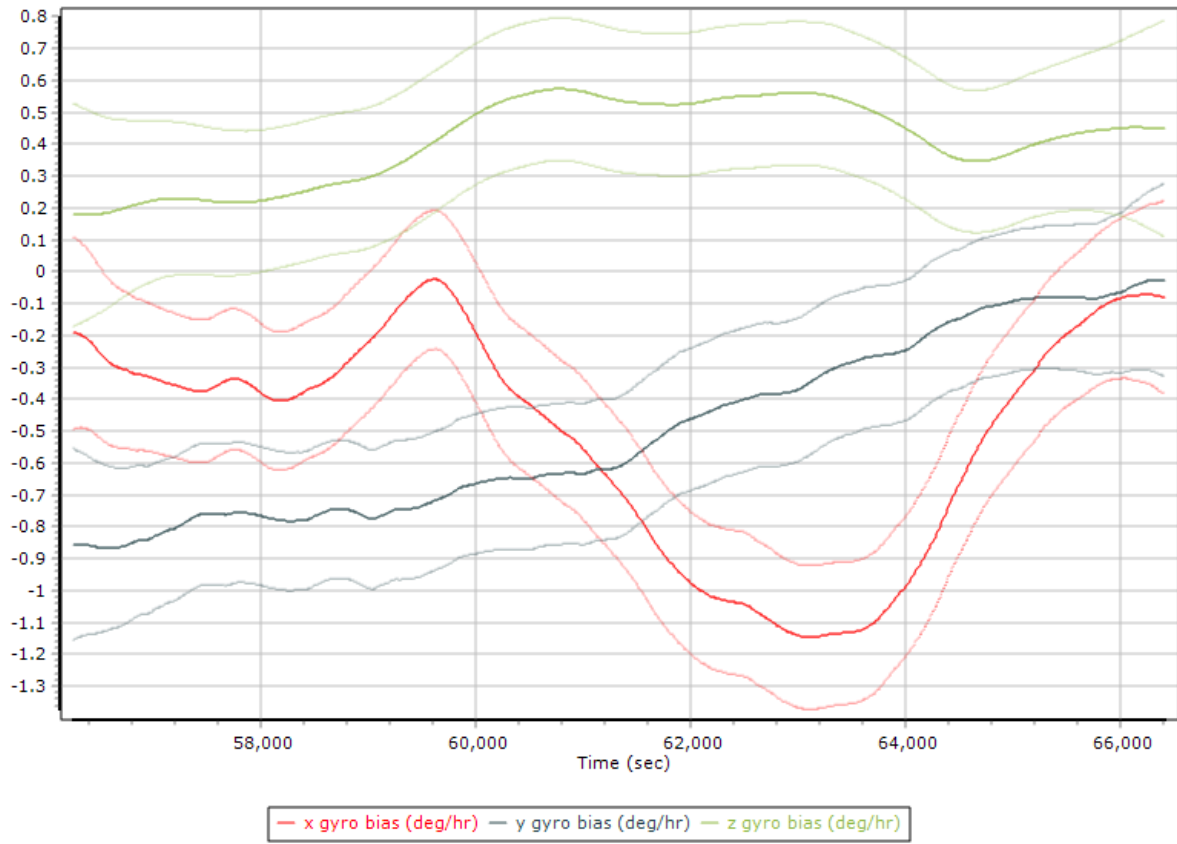
CAU18056A

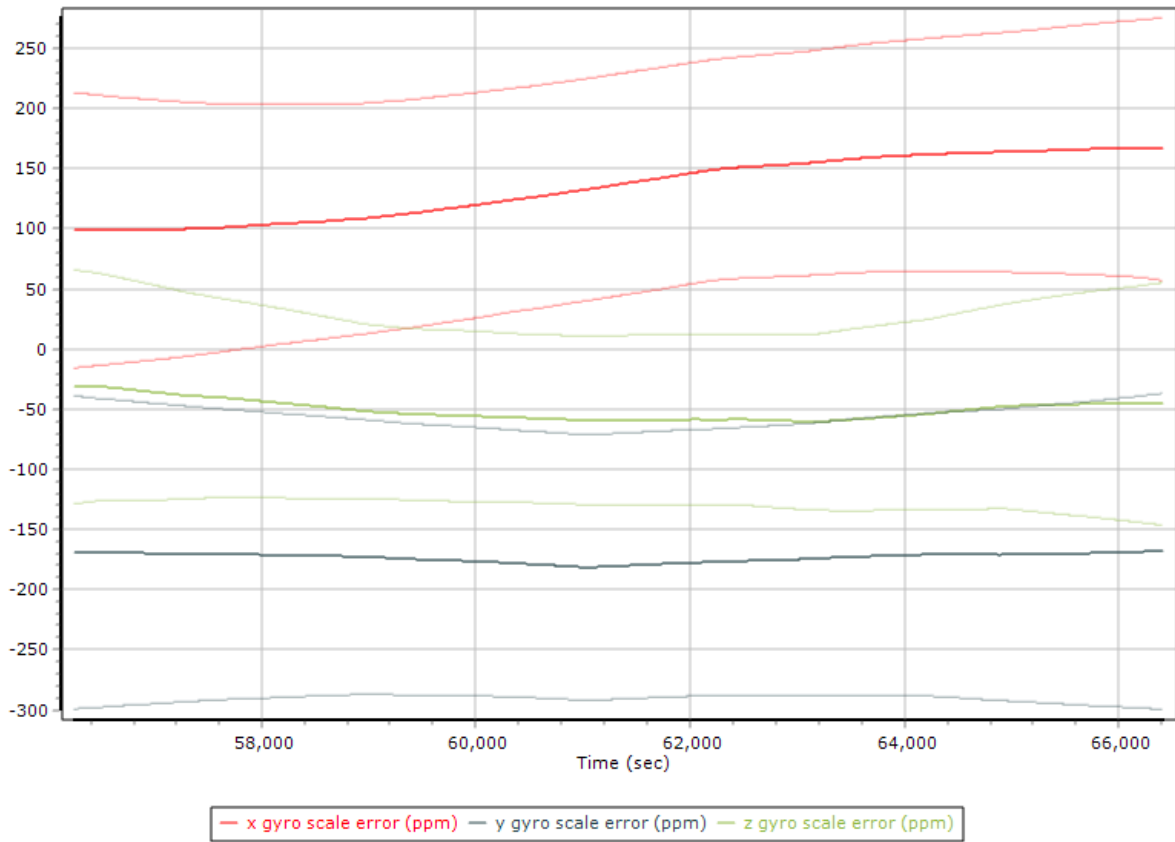












Project Settings [X]

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

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

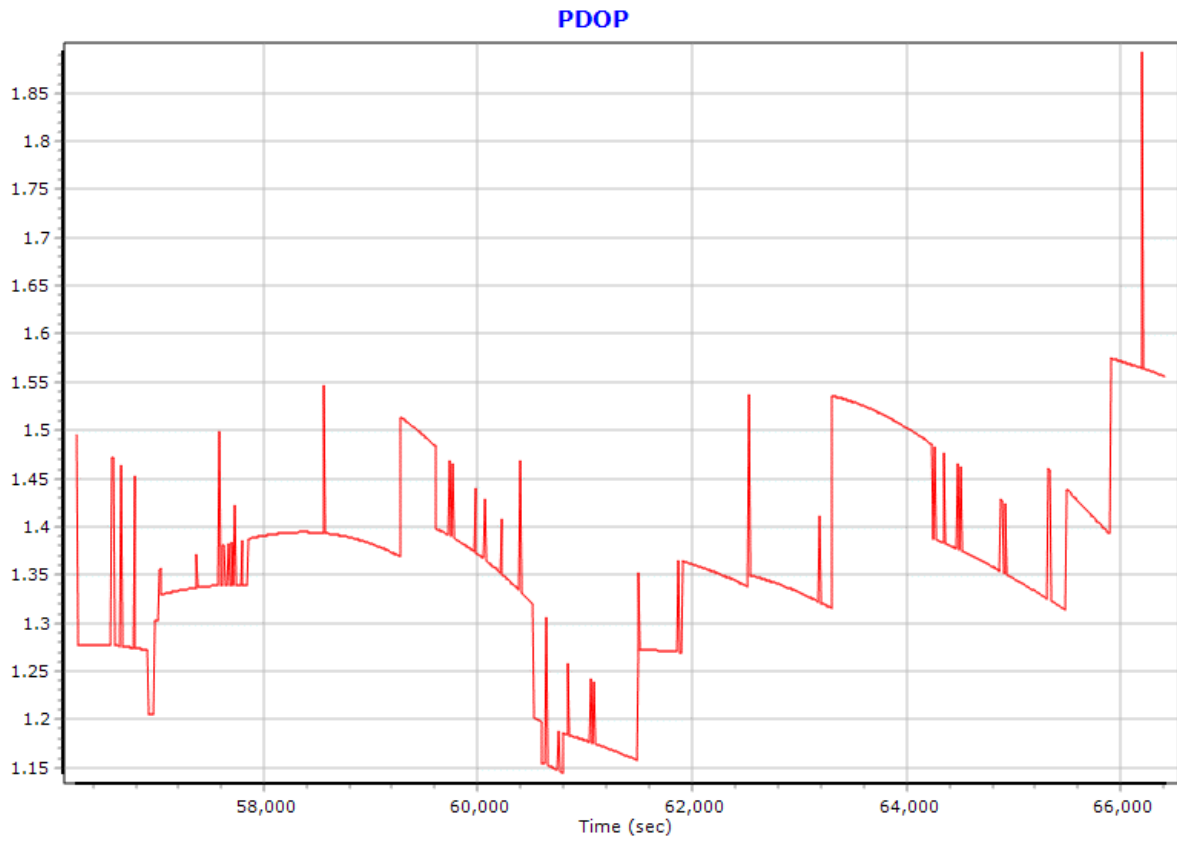
Aircraft to Reference Mounting Angles

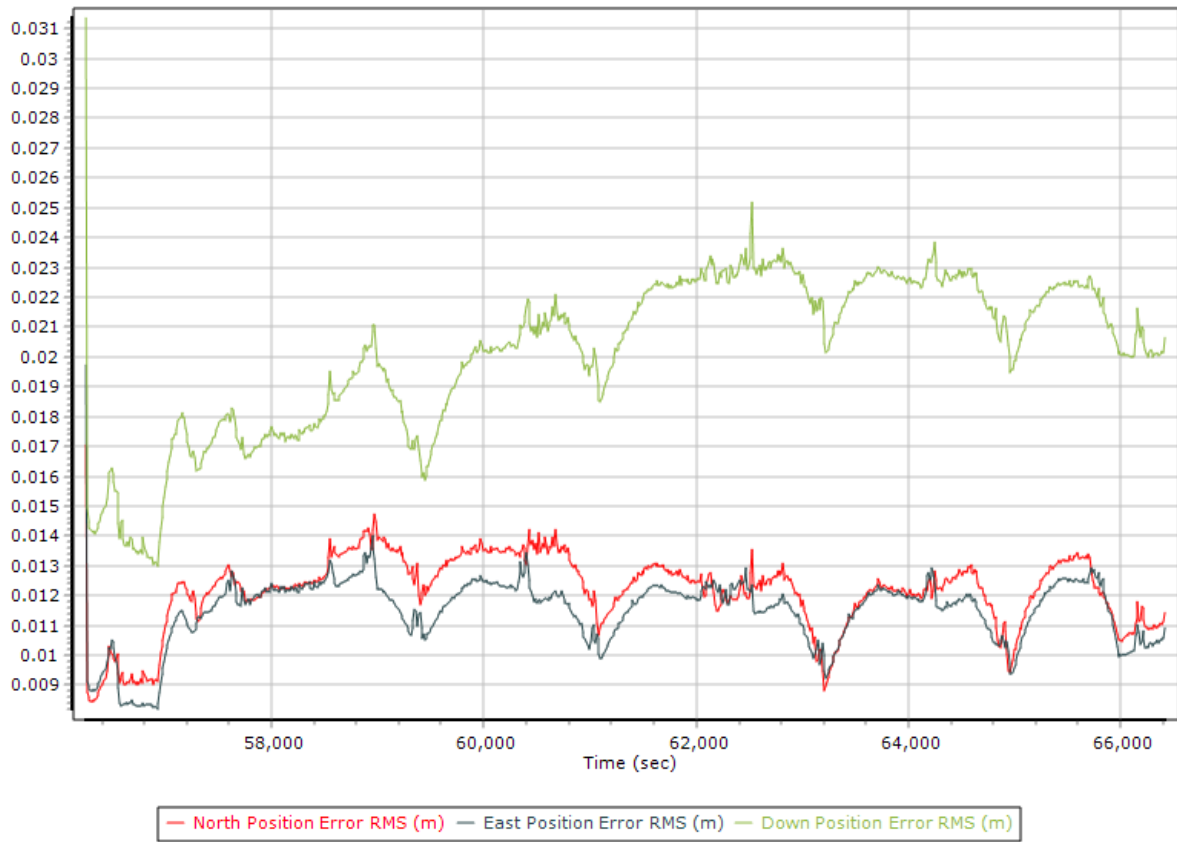
X:

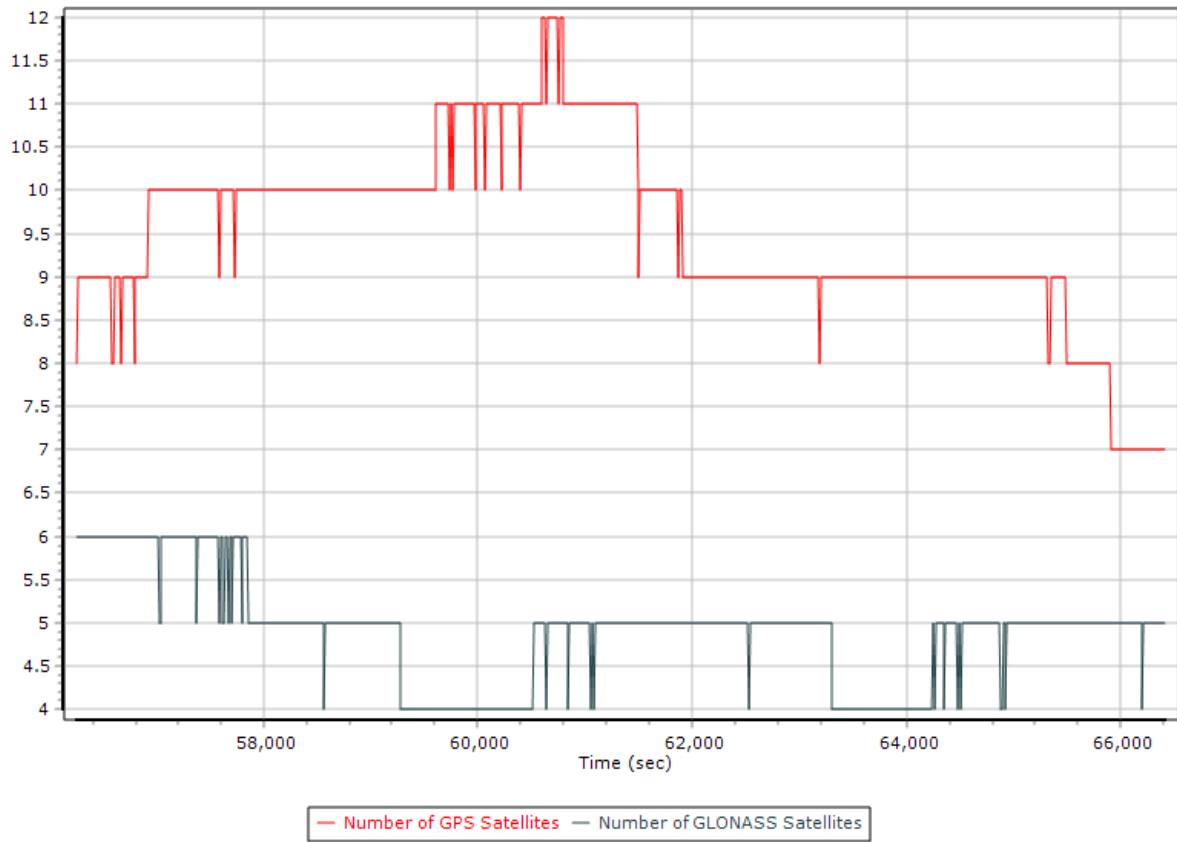
Y:

Z:

OK Cancel









Project Settings [X]

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

Timing

Start: 52074.000
 End: 68752.000
 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

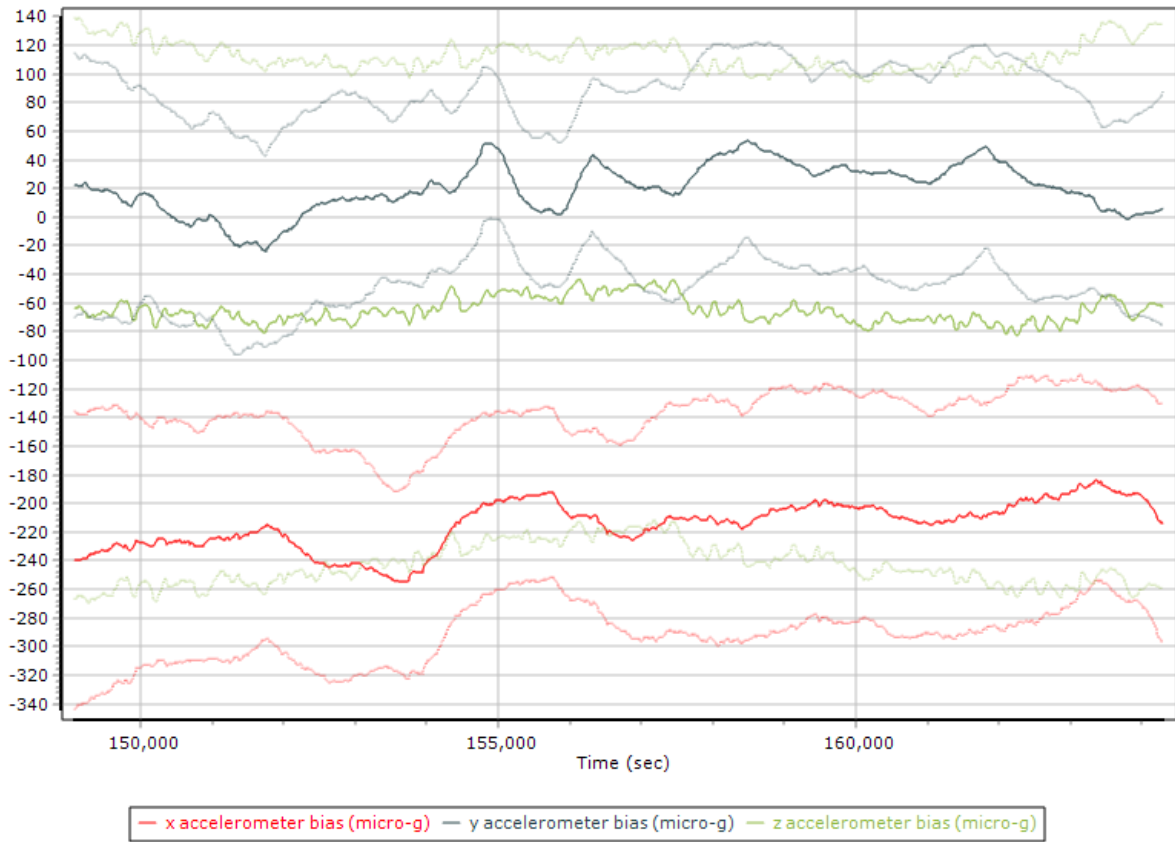
Processable Time Windows

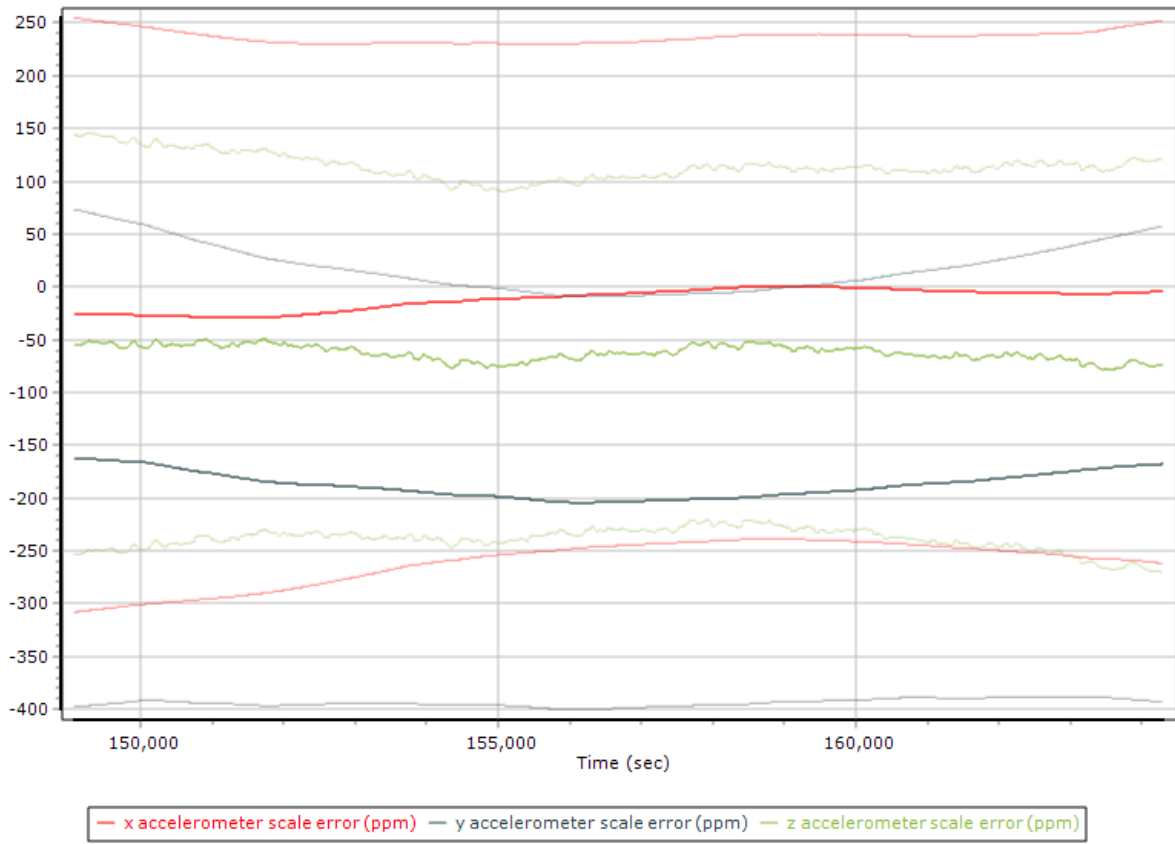
Start after launch Wait Time: 4.000 sec

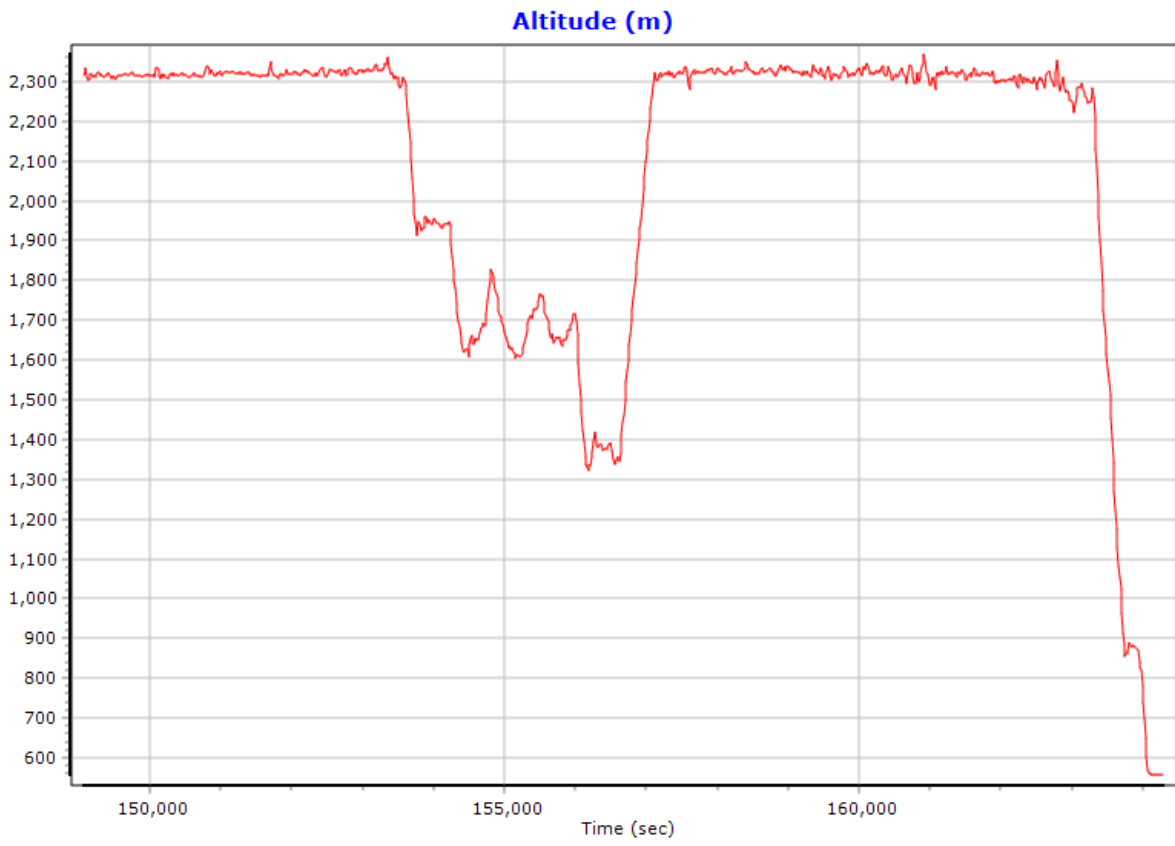
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	52074.000	68752.000	16678.000	End of file

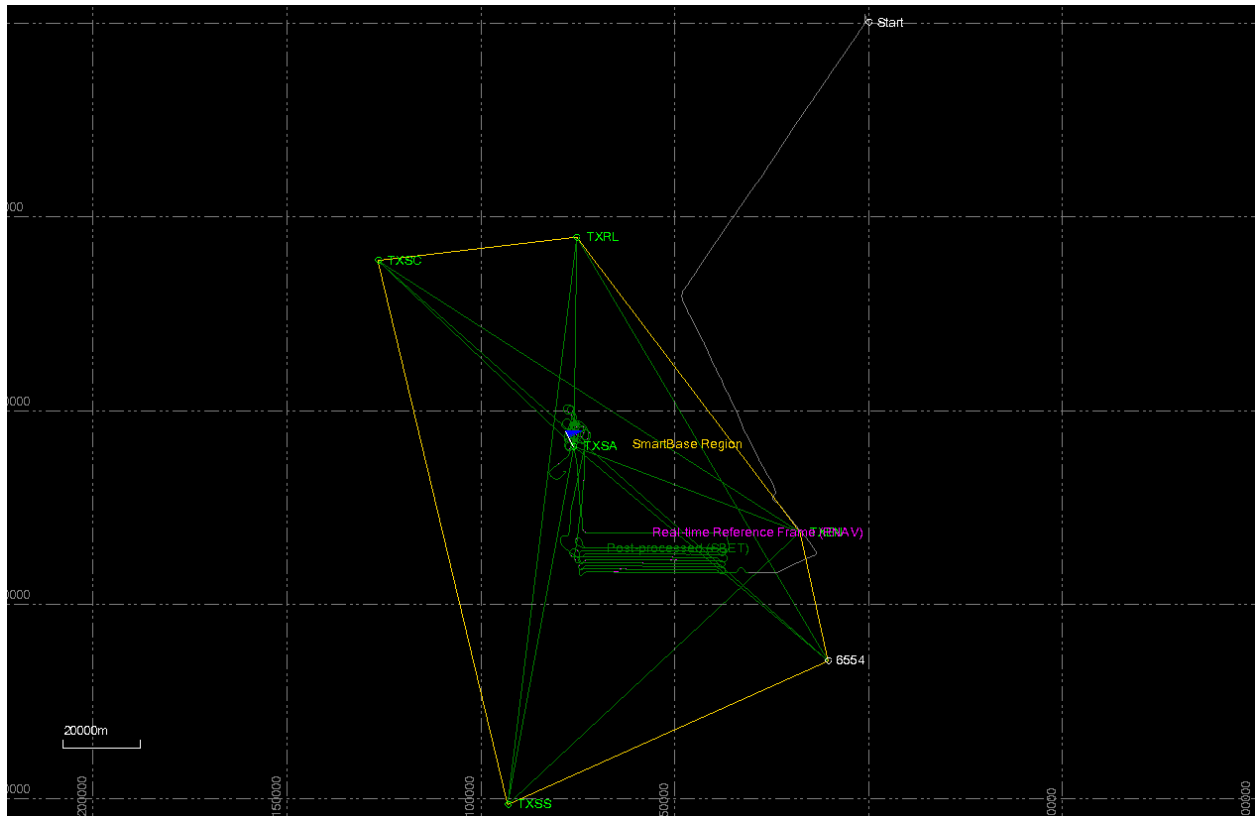
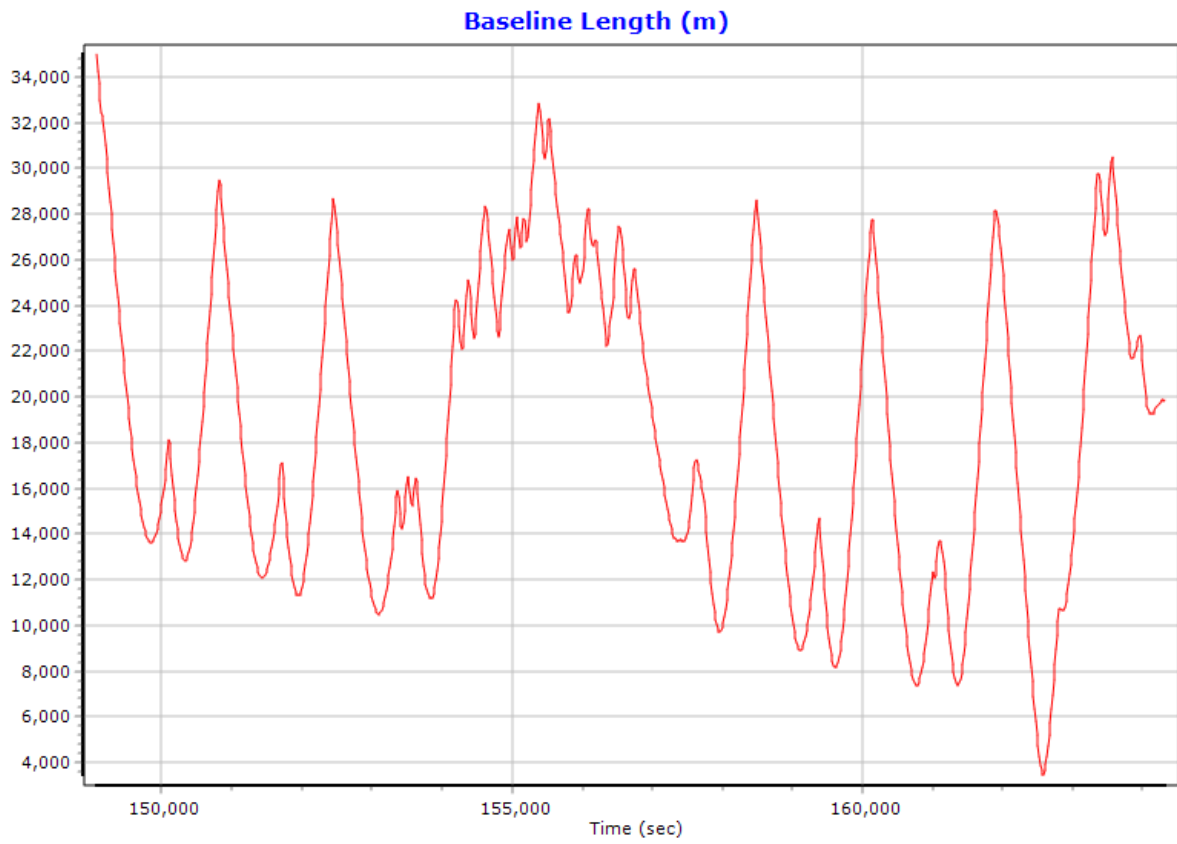
OK Cancel

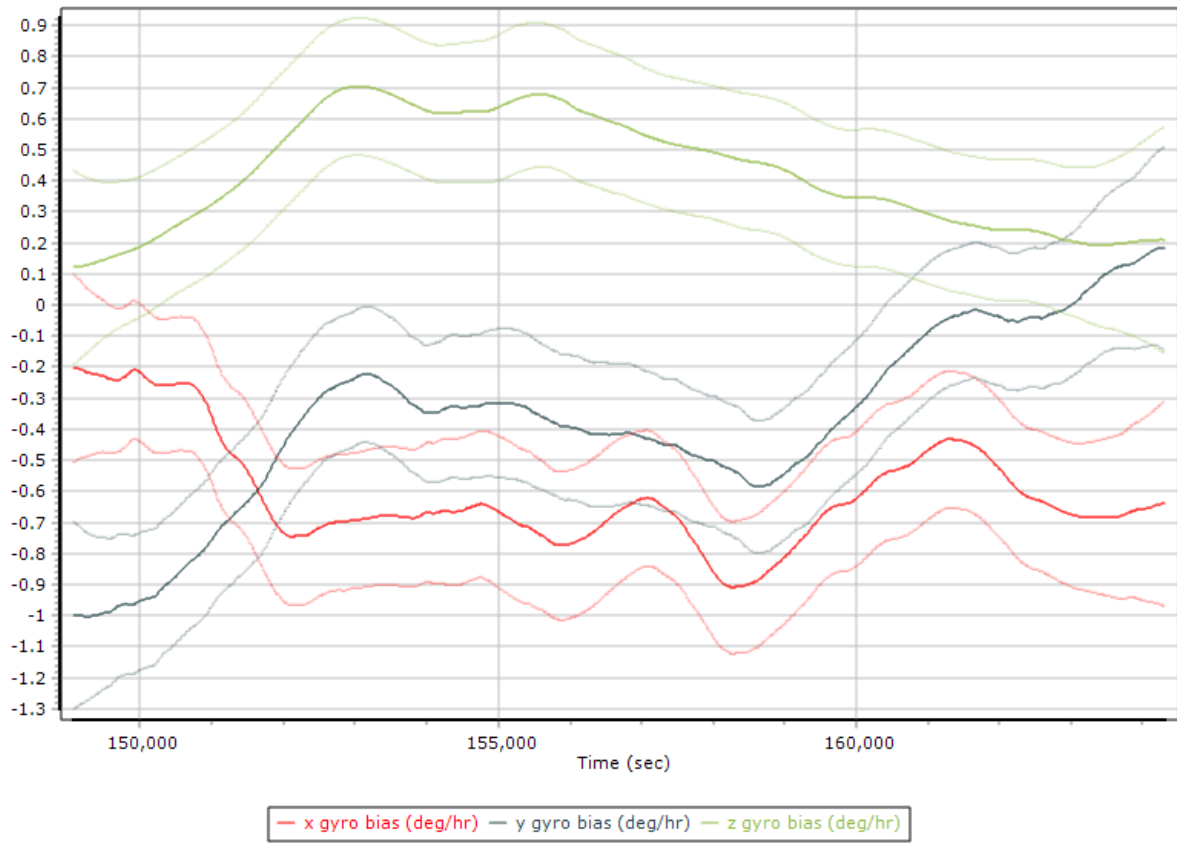
CAU18057A

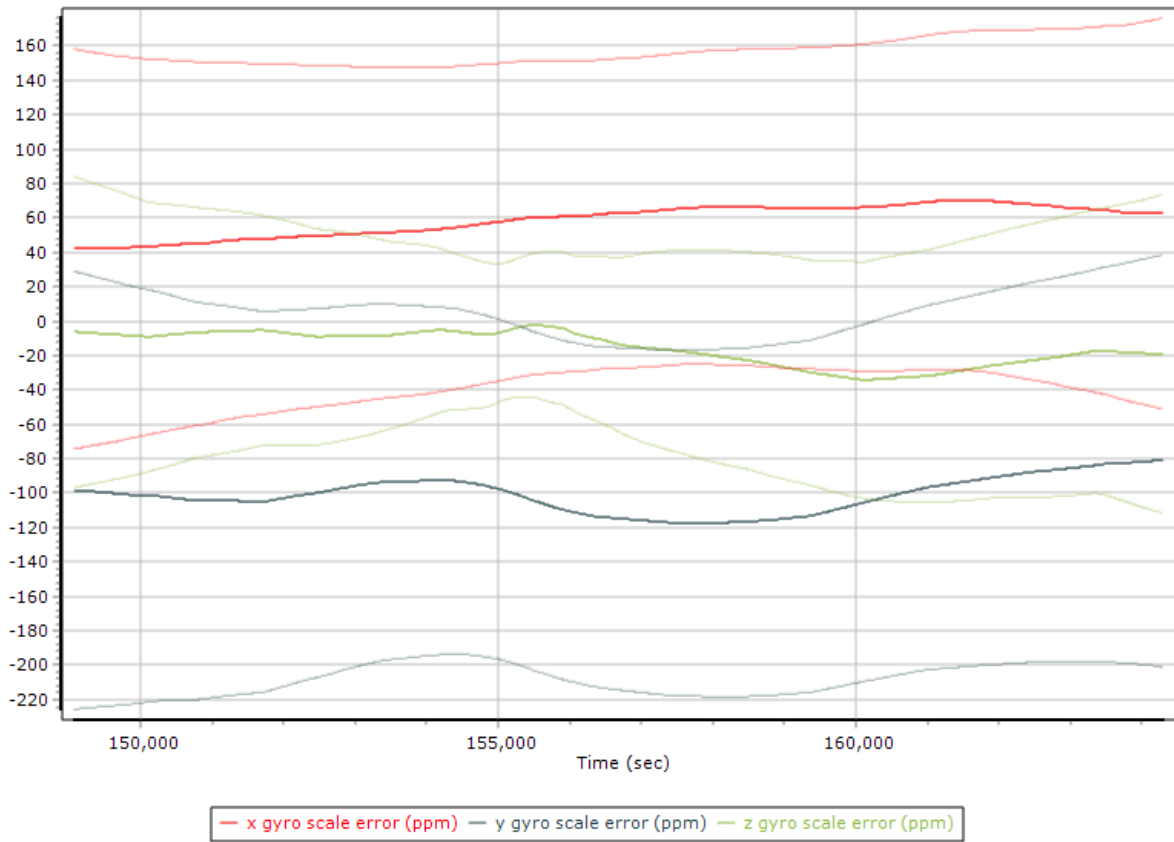












Project Settings [X]

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

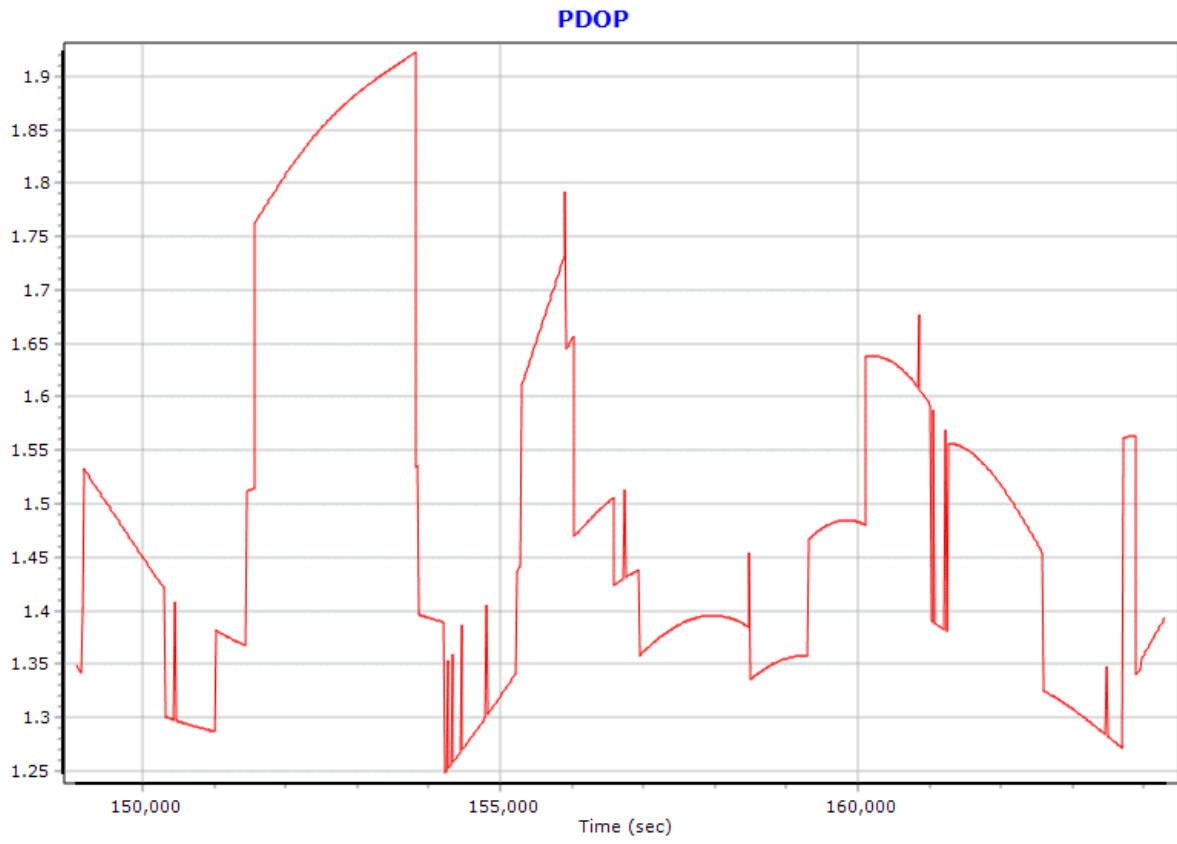
Aircraft to Reference Mounting Angles

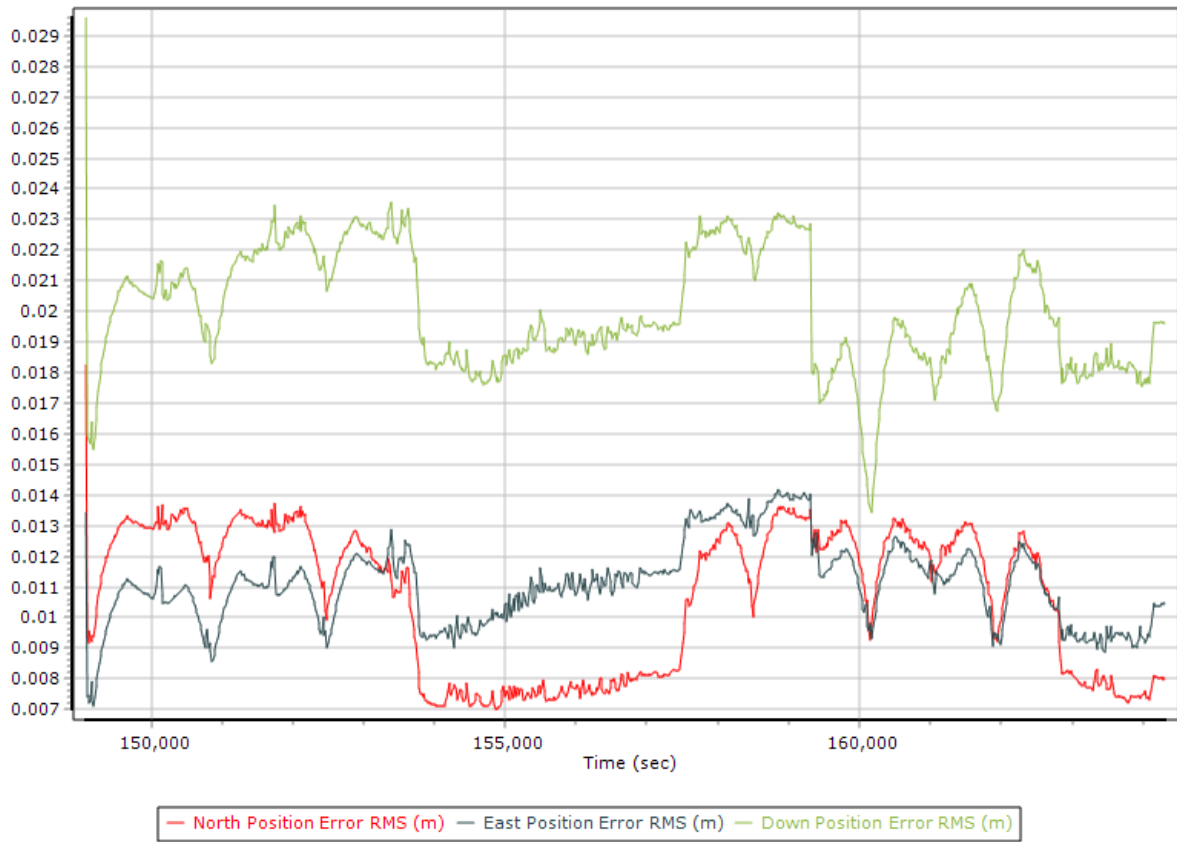
X:

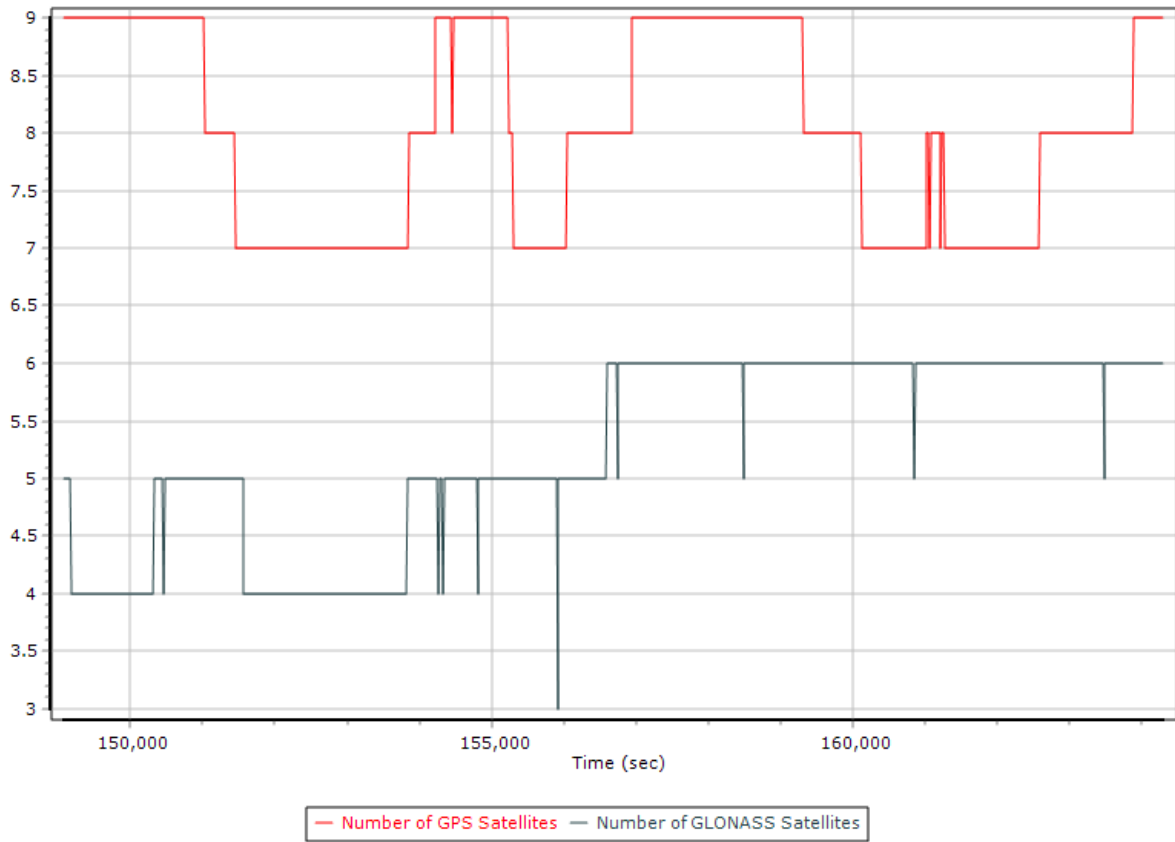
Y:

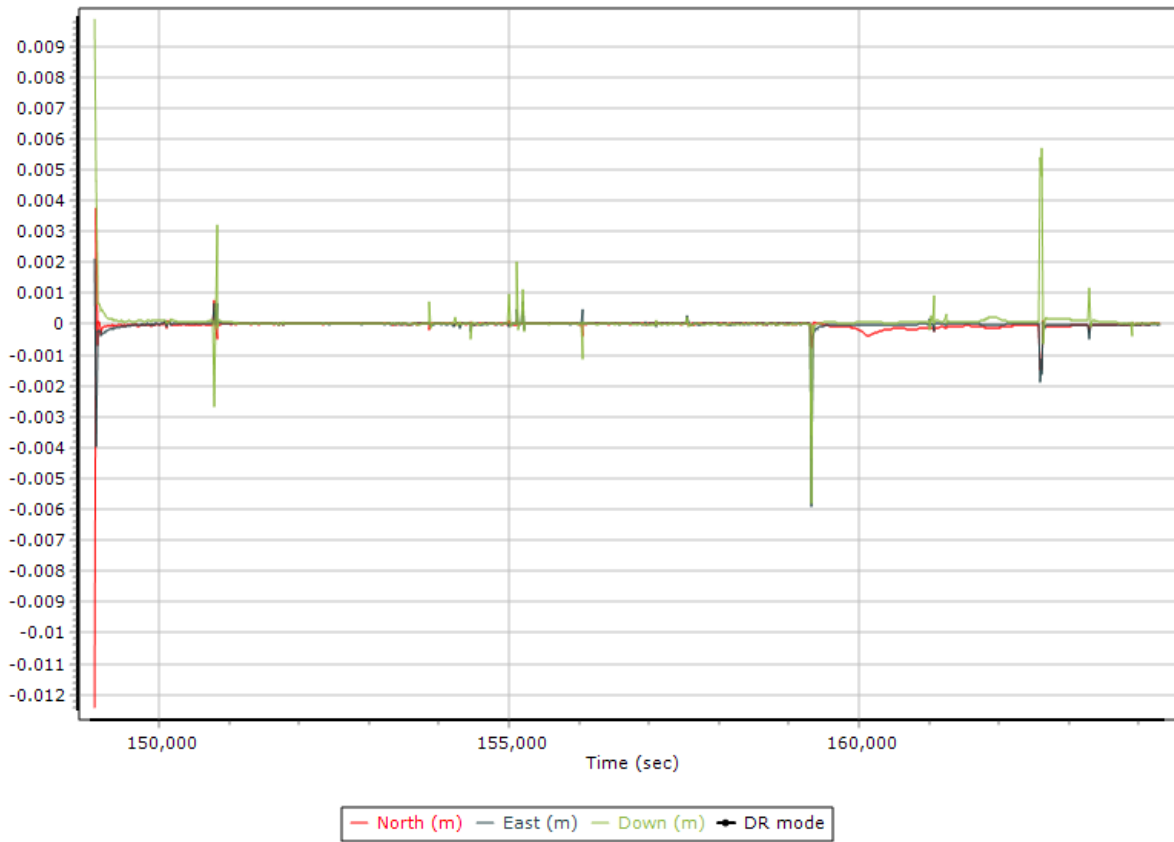
Z:

OK Cancel









Project Settings

- 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: 144437.000
End: 164325.000

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

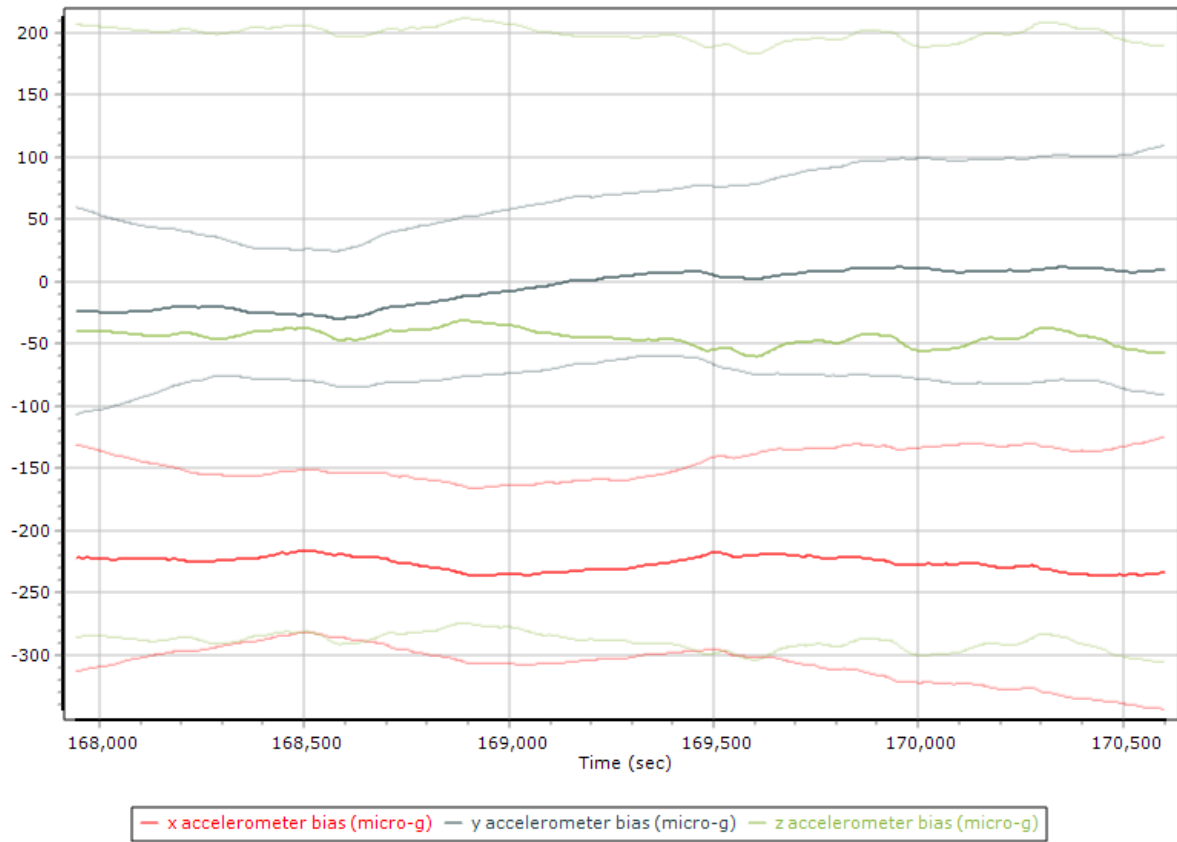
Processable Time Windows

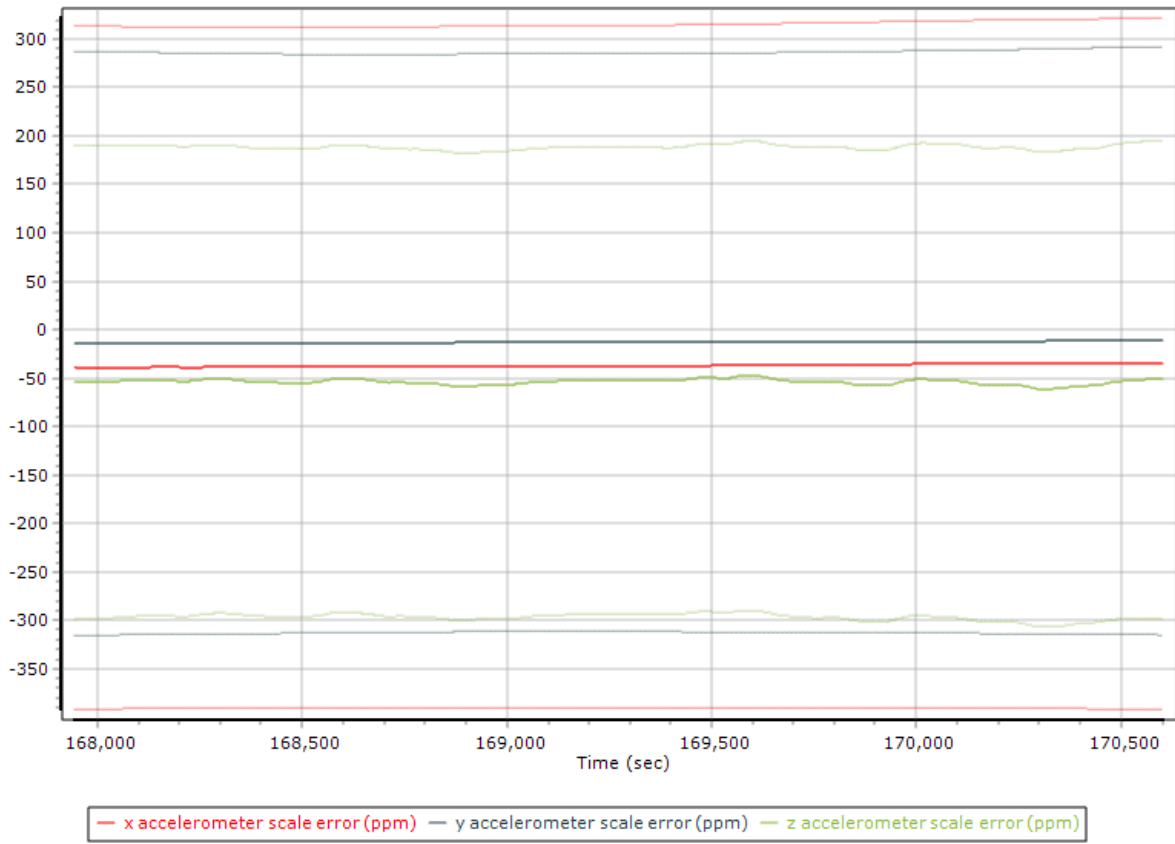
Start after launch Wait Time: 4.000 sec

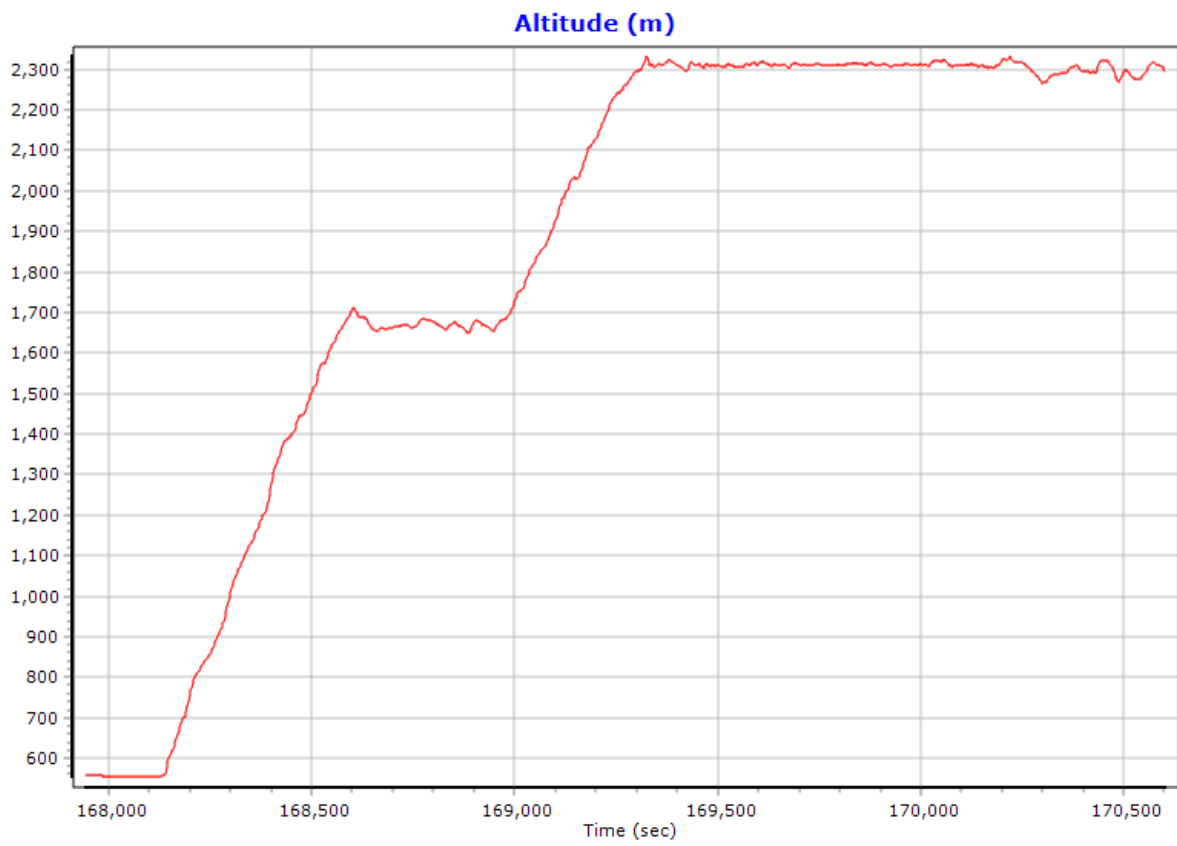
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	144437.000	164325.000	19888.000	End of file

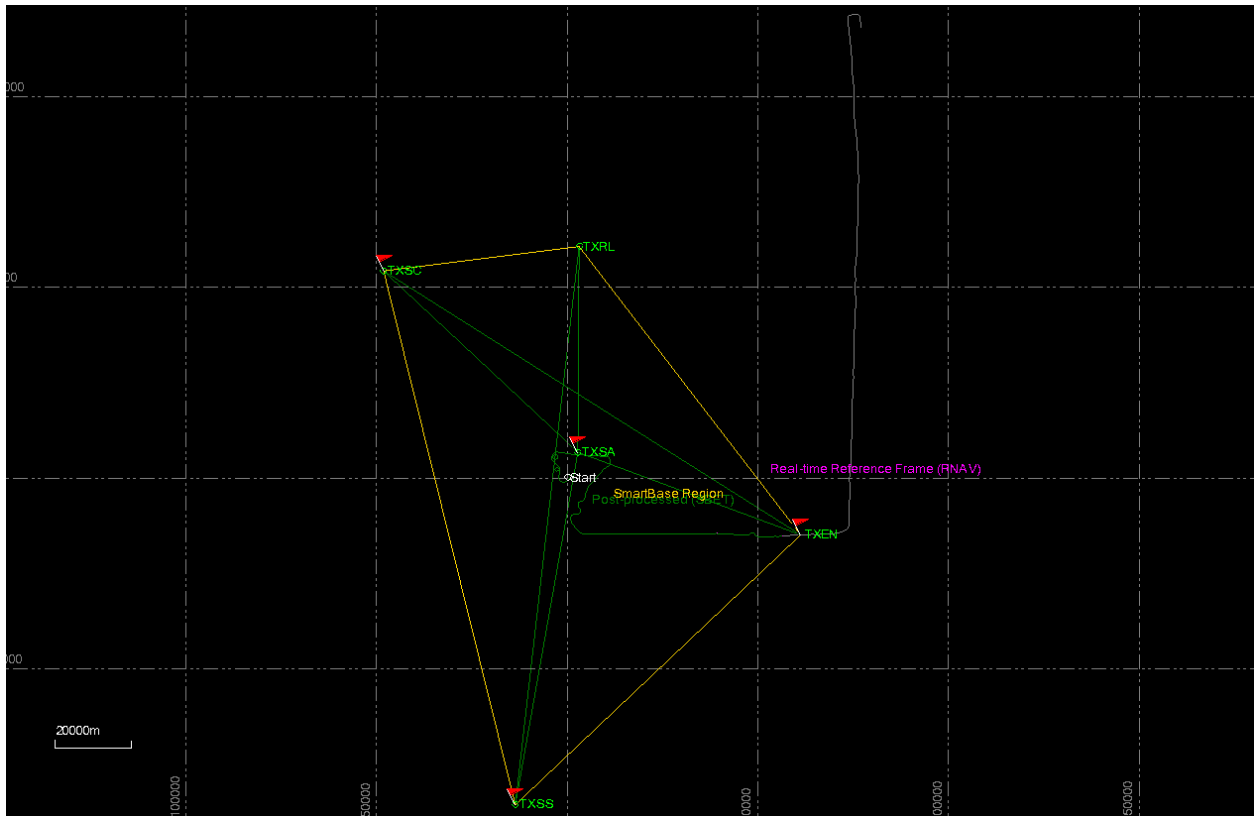
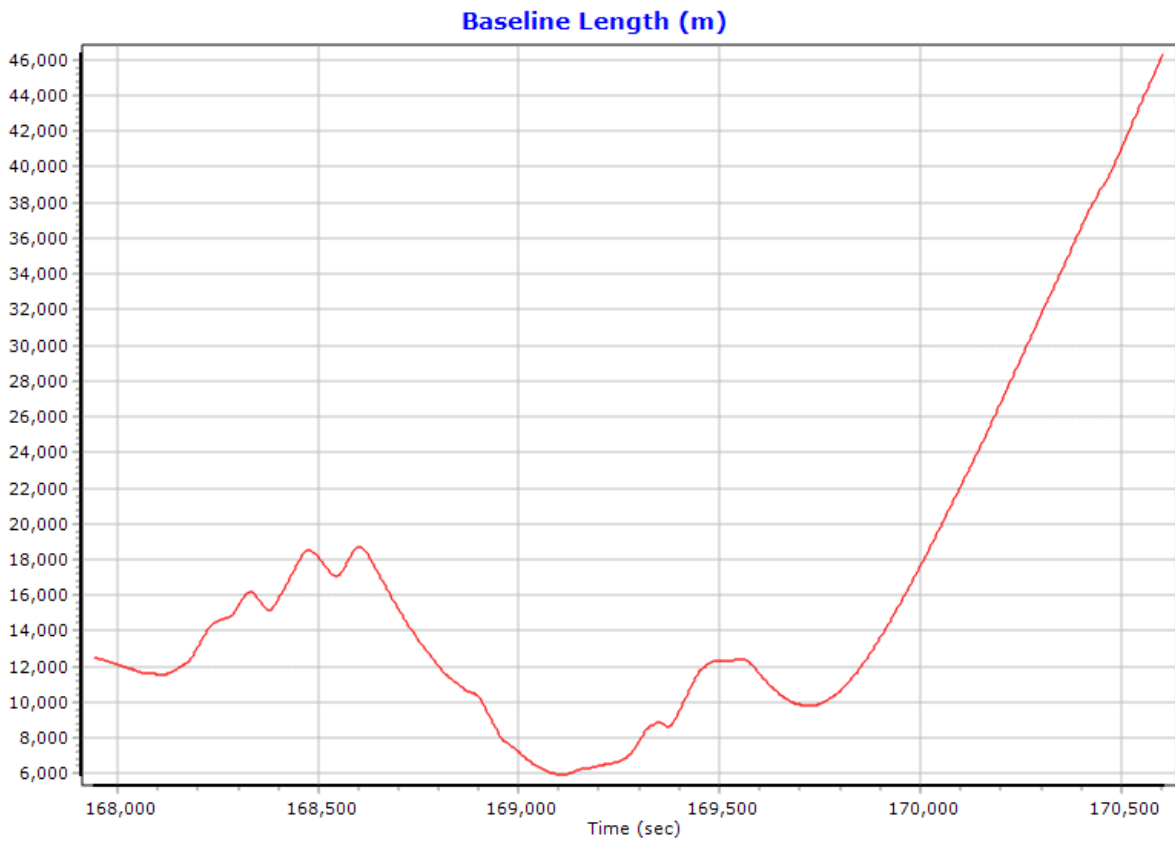
OK Cancel

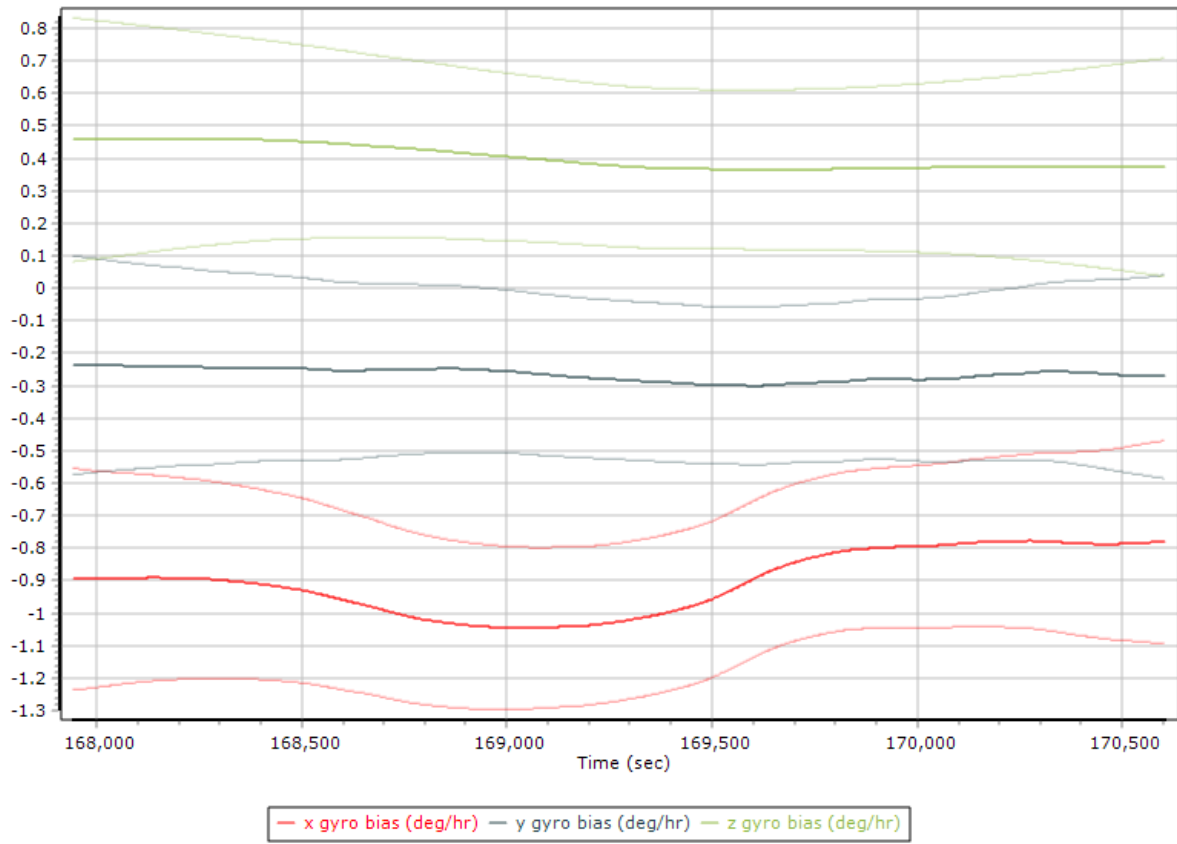
CAU18057B

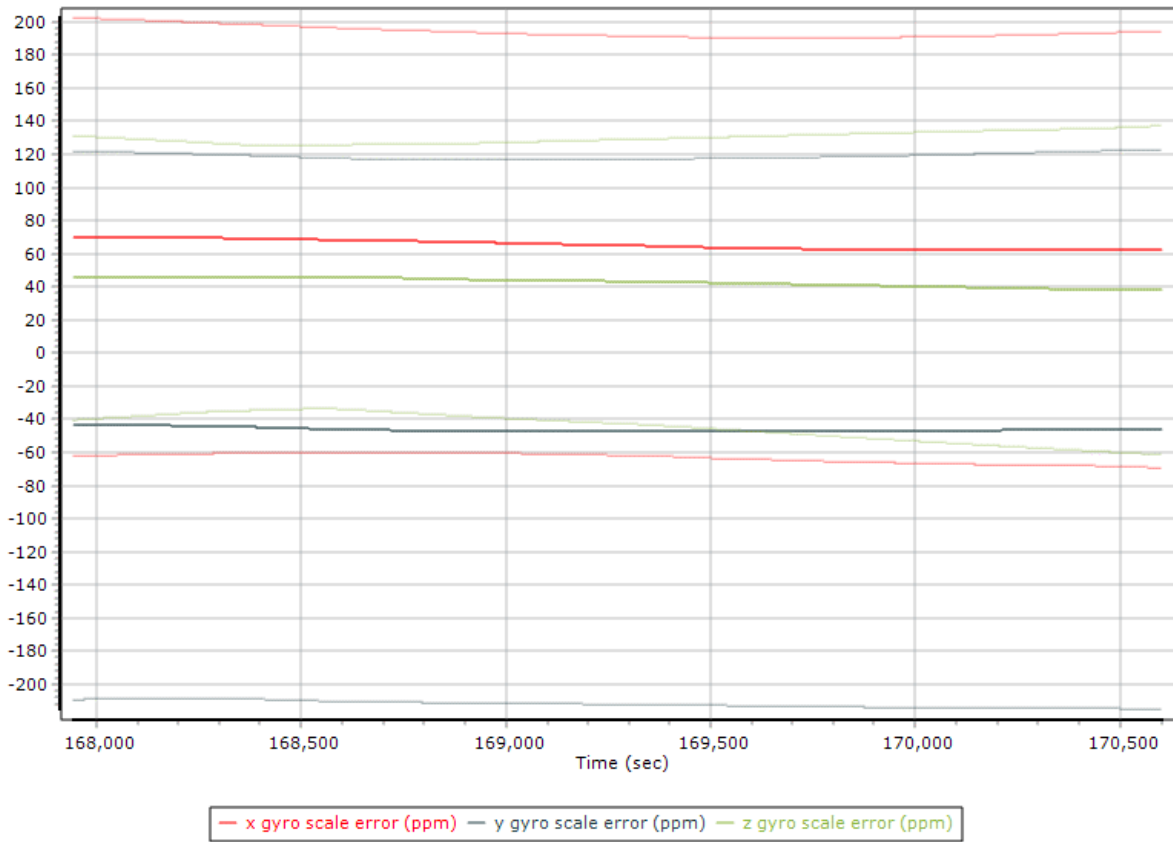












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

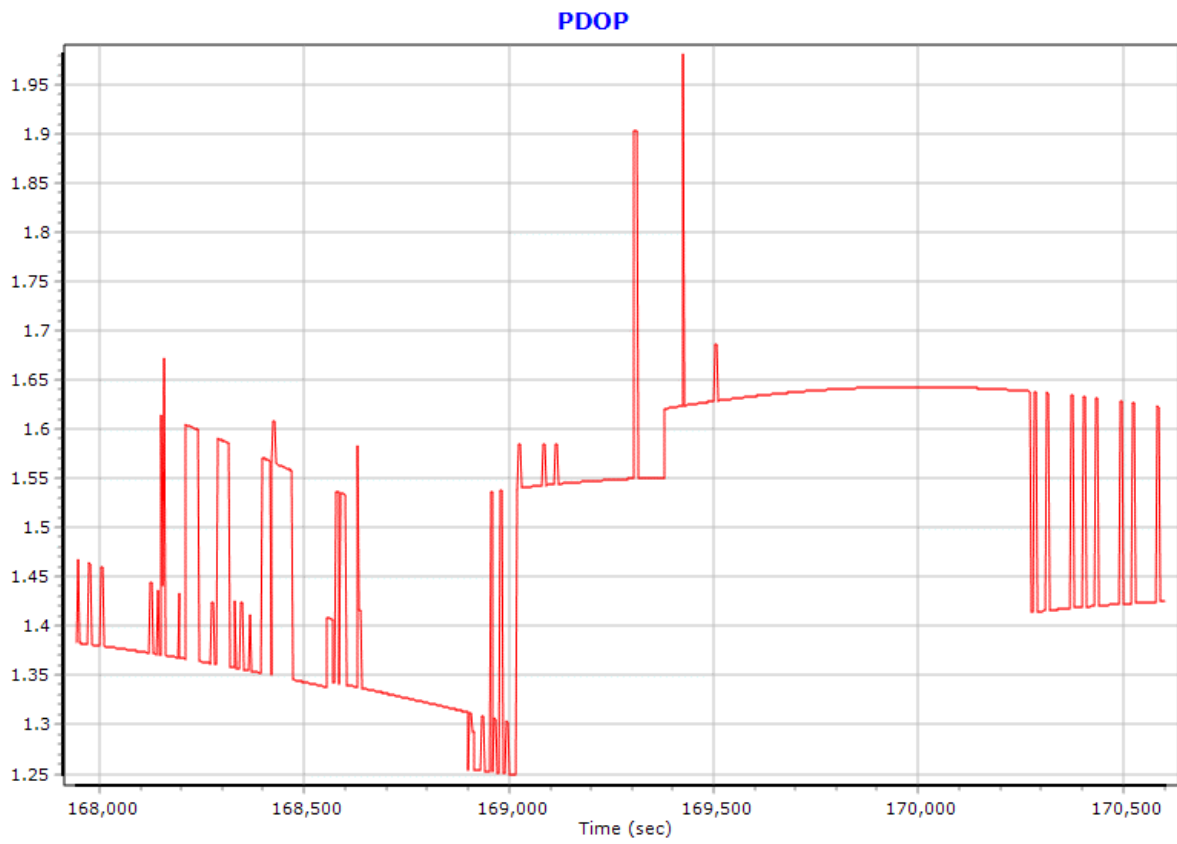
Aircraft to Reference Mounting Angles

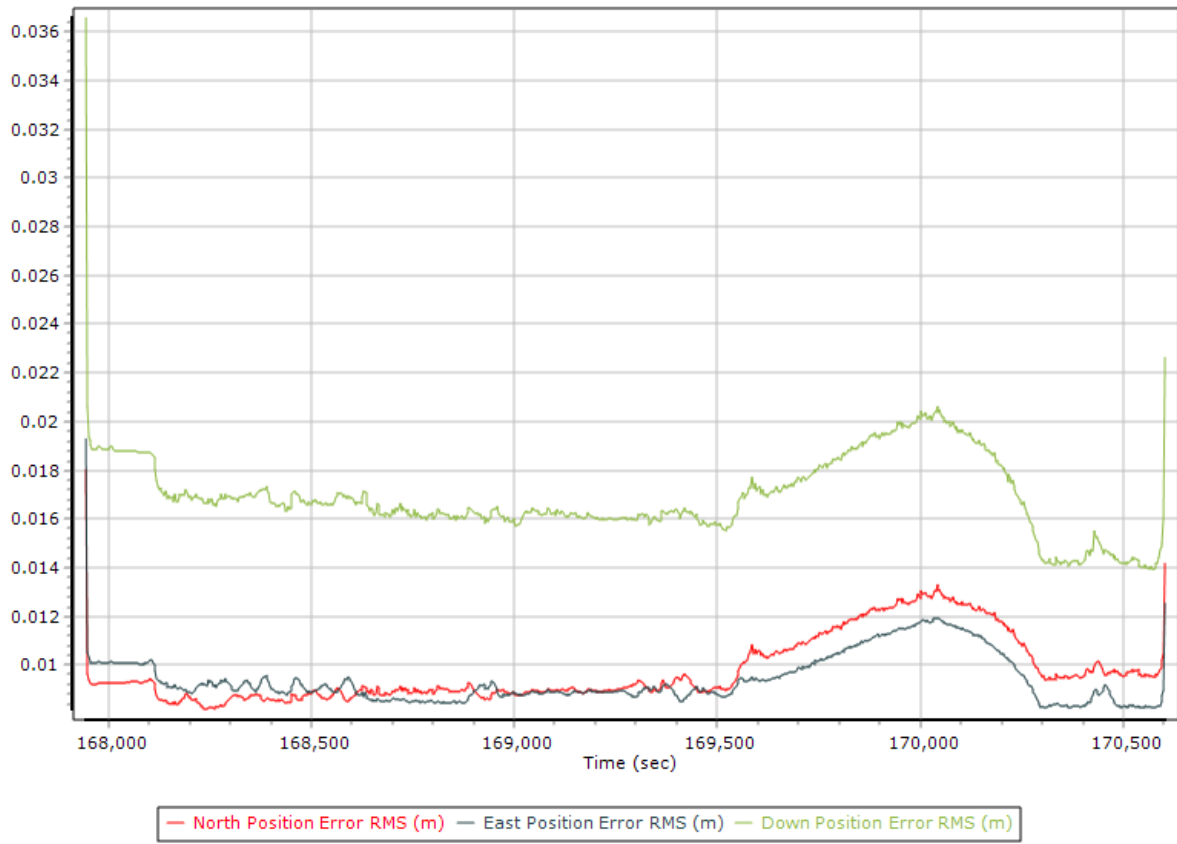
X:

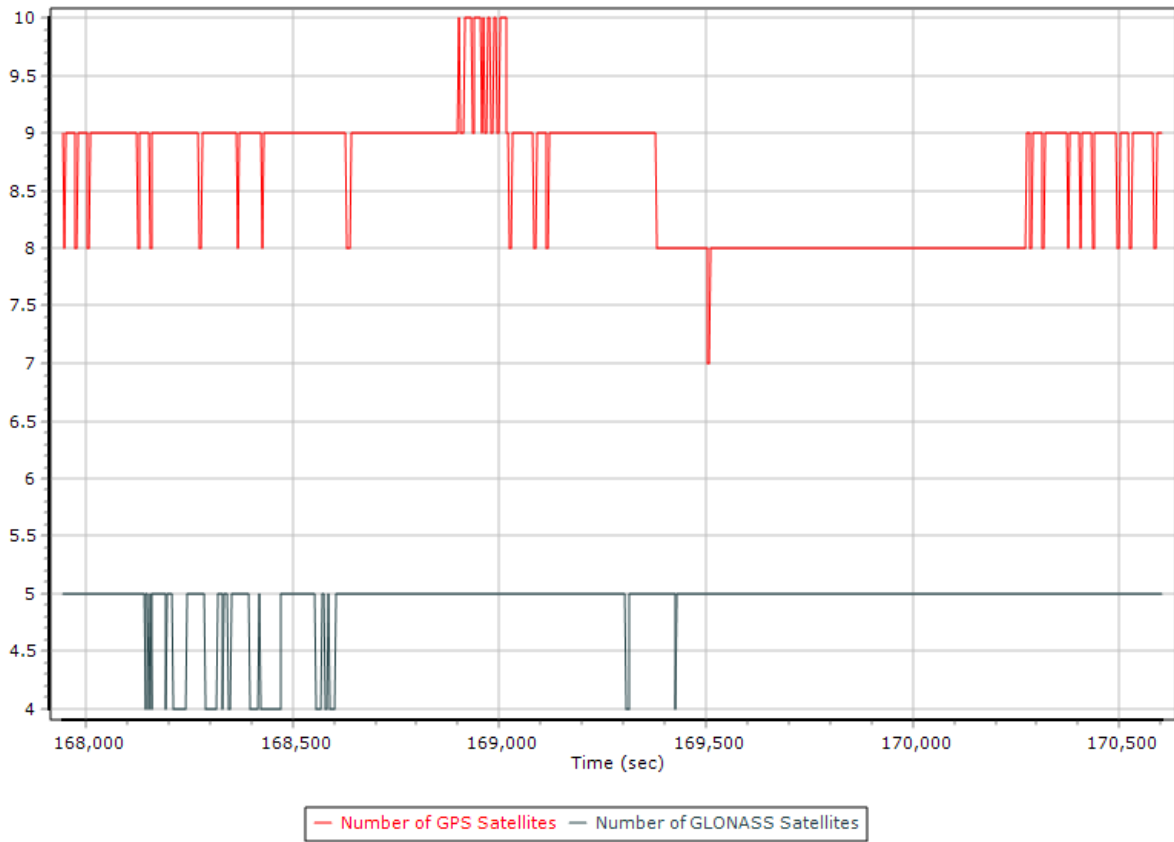
Y:

Z:

OK Cancel









Project Settings

- 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: 167515.000
End: 173545.000

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

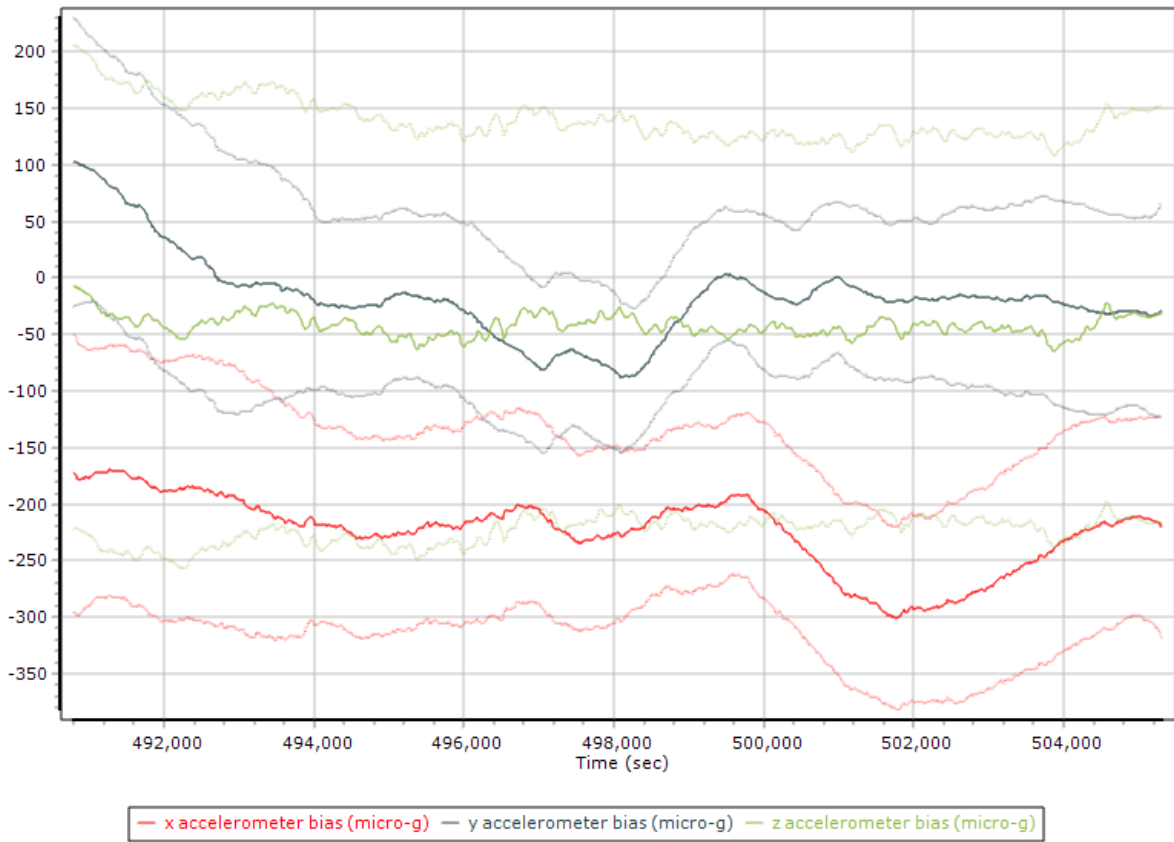
Processable Time Windows

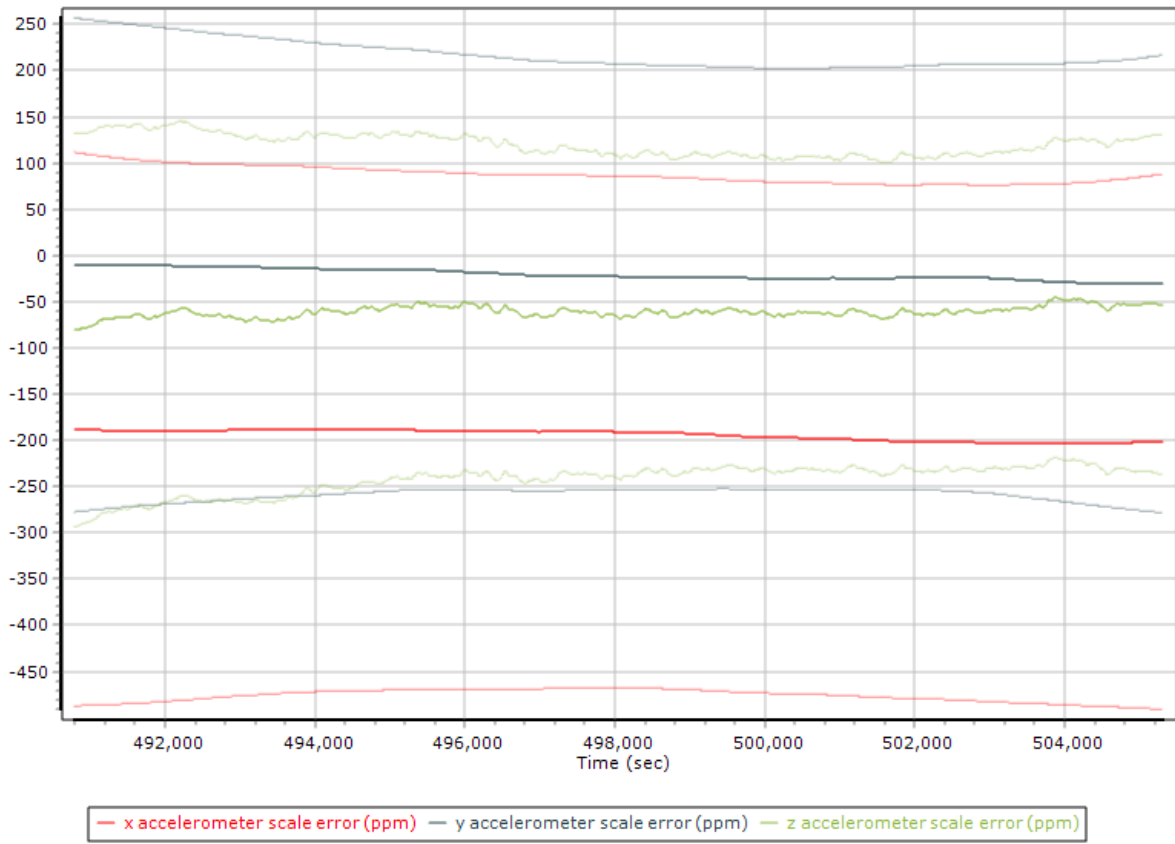
Start after launch Wait Time: 4.000 sec

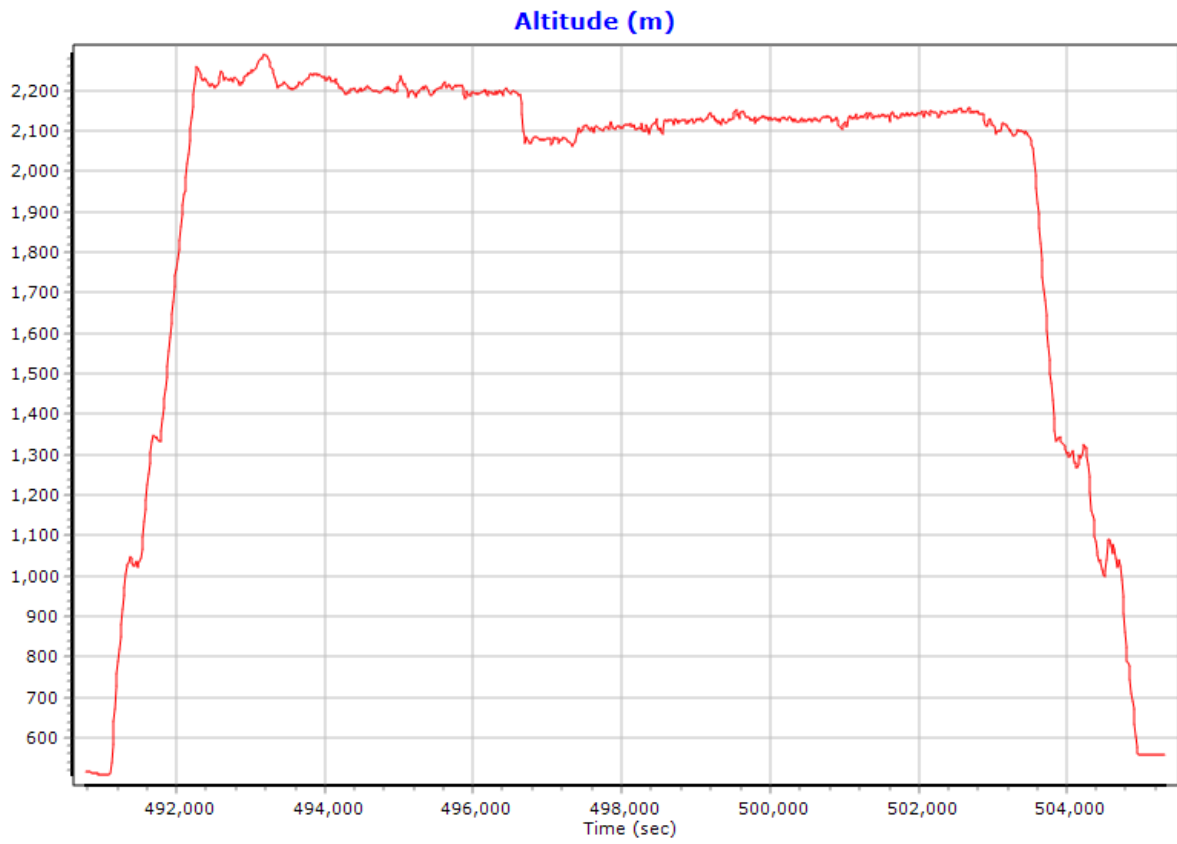
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	167515.000	173545.000	6030.000	End of file

OK Cancel

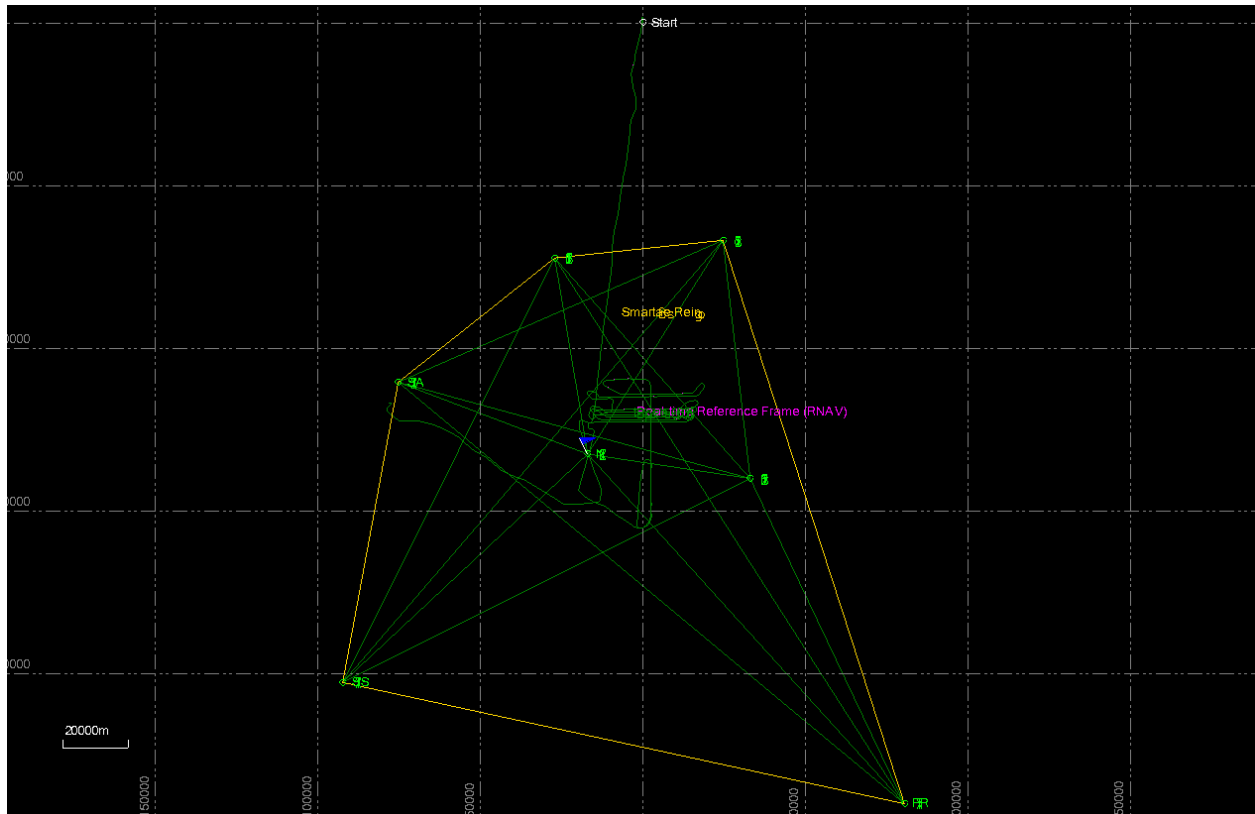
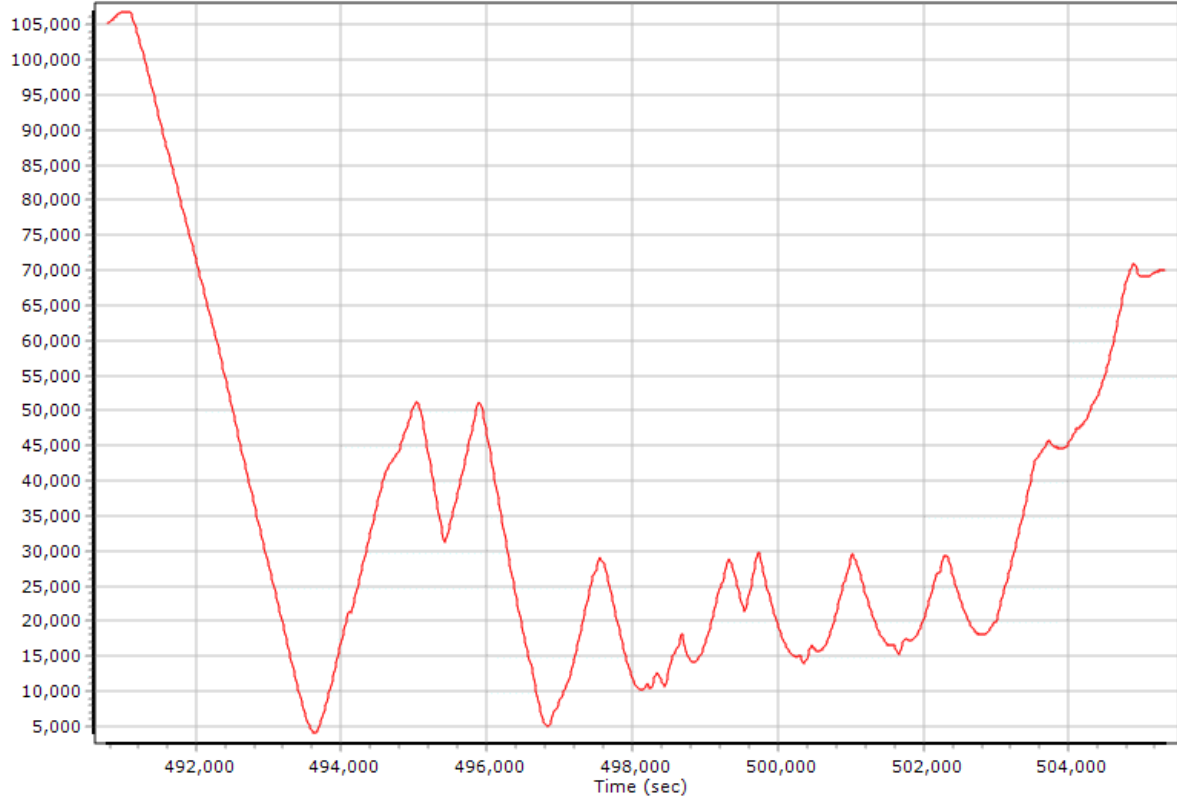
CAU18061A

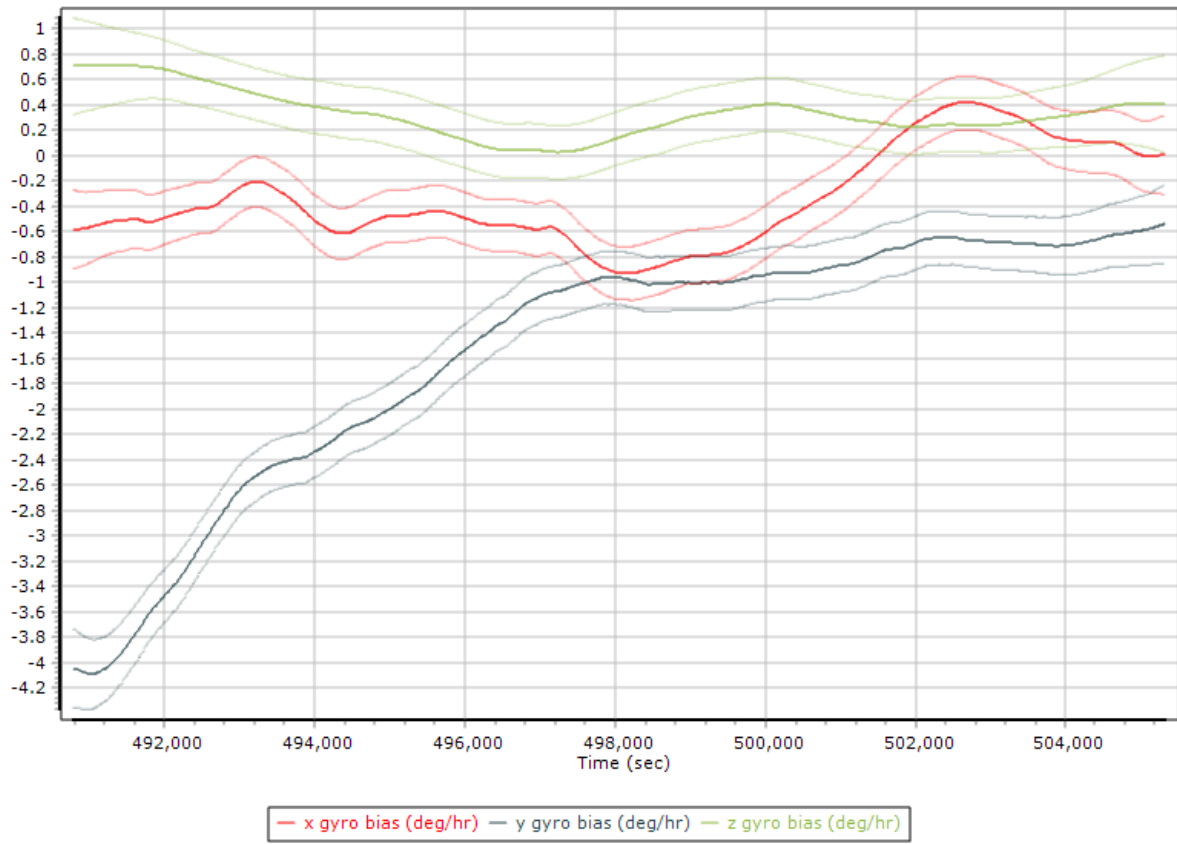


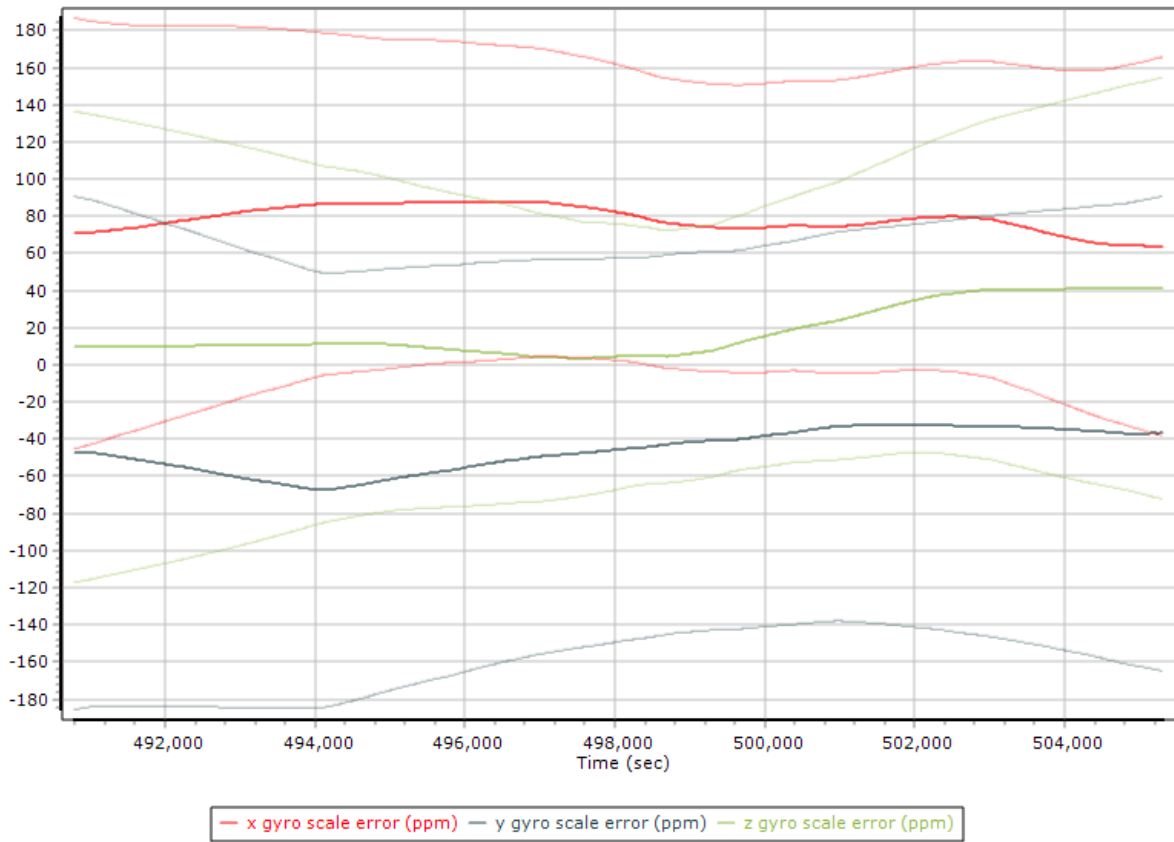




Baseline Length (m)







Project Settings

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation: (Selected)

<3cm 10cm 50cm 1m 10m

Reference to IMU Mounting Angles

X:

Y:

Z:

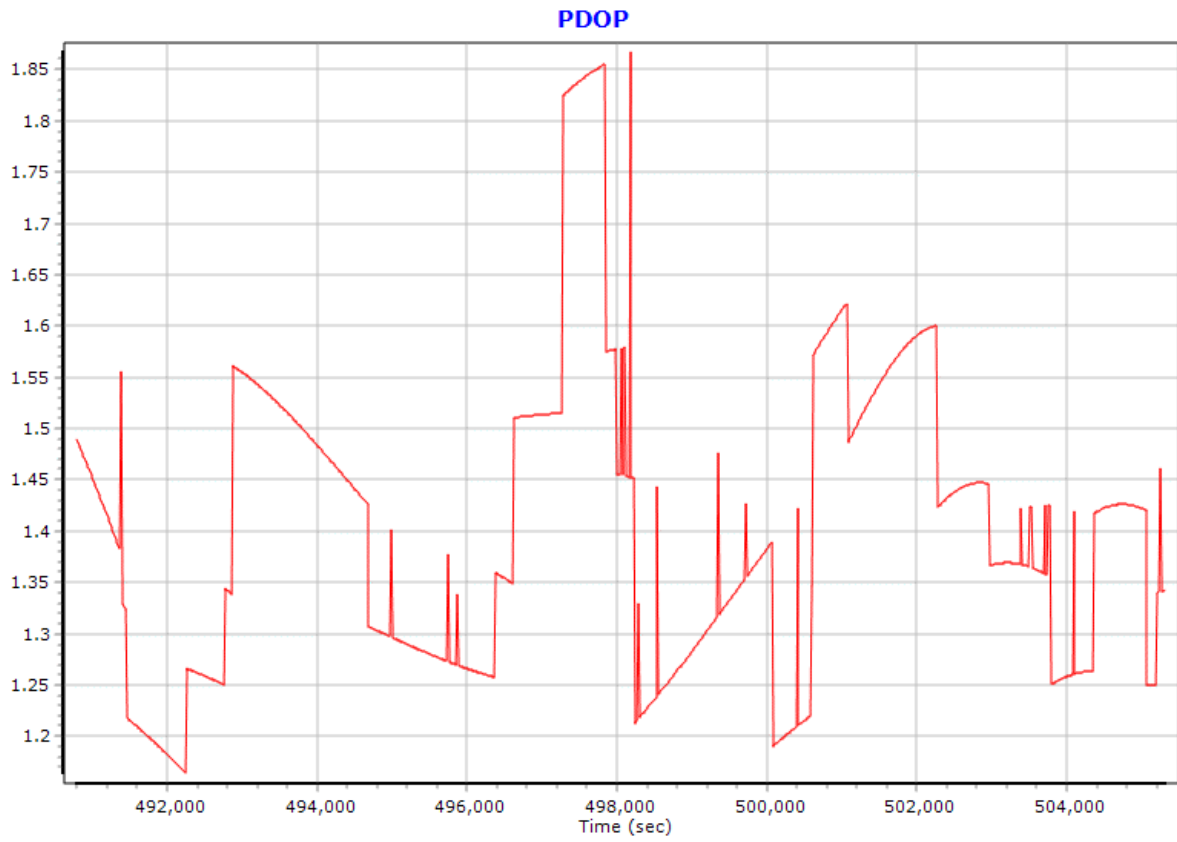
Aircraft to Reference Mounting Angles

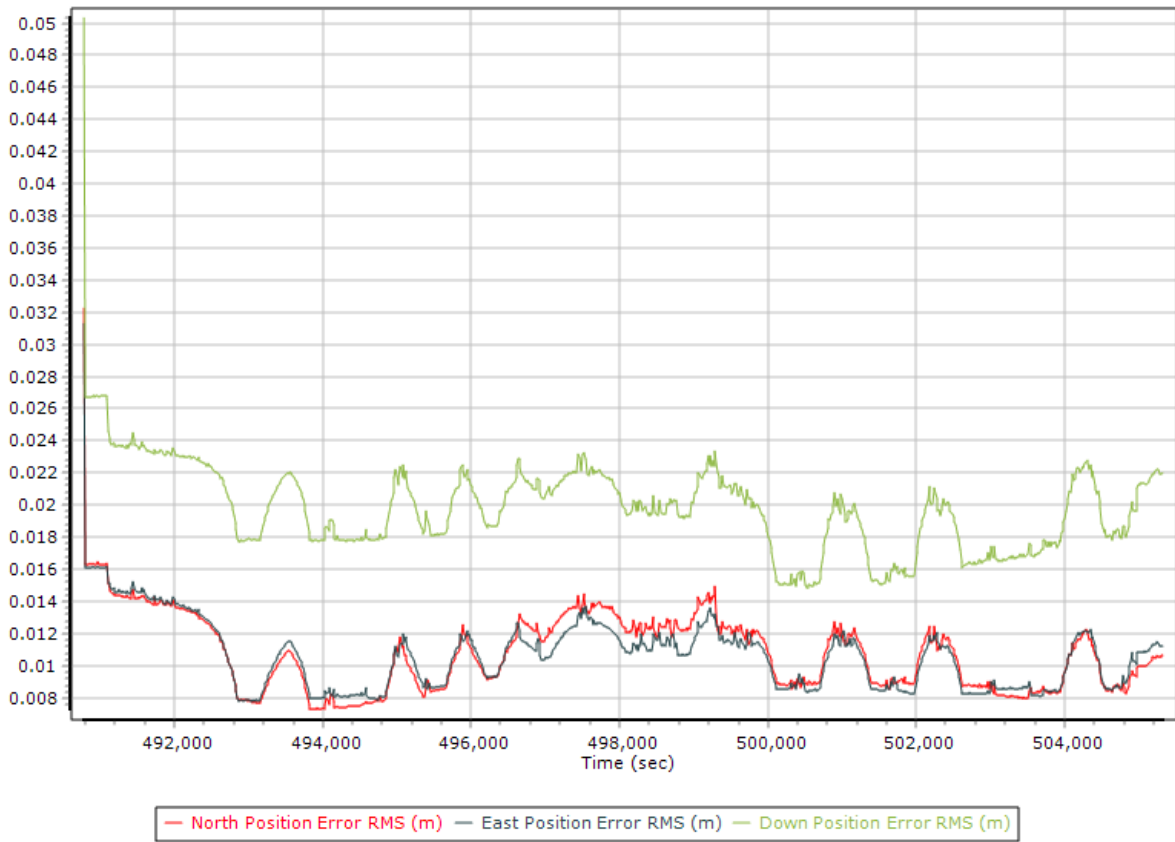
X:

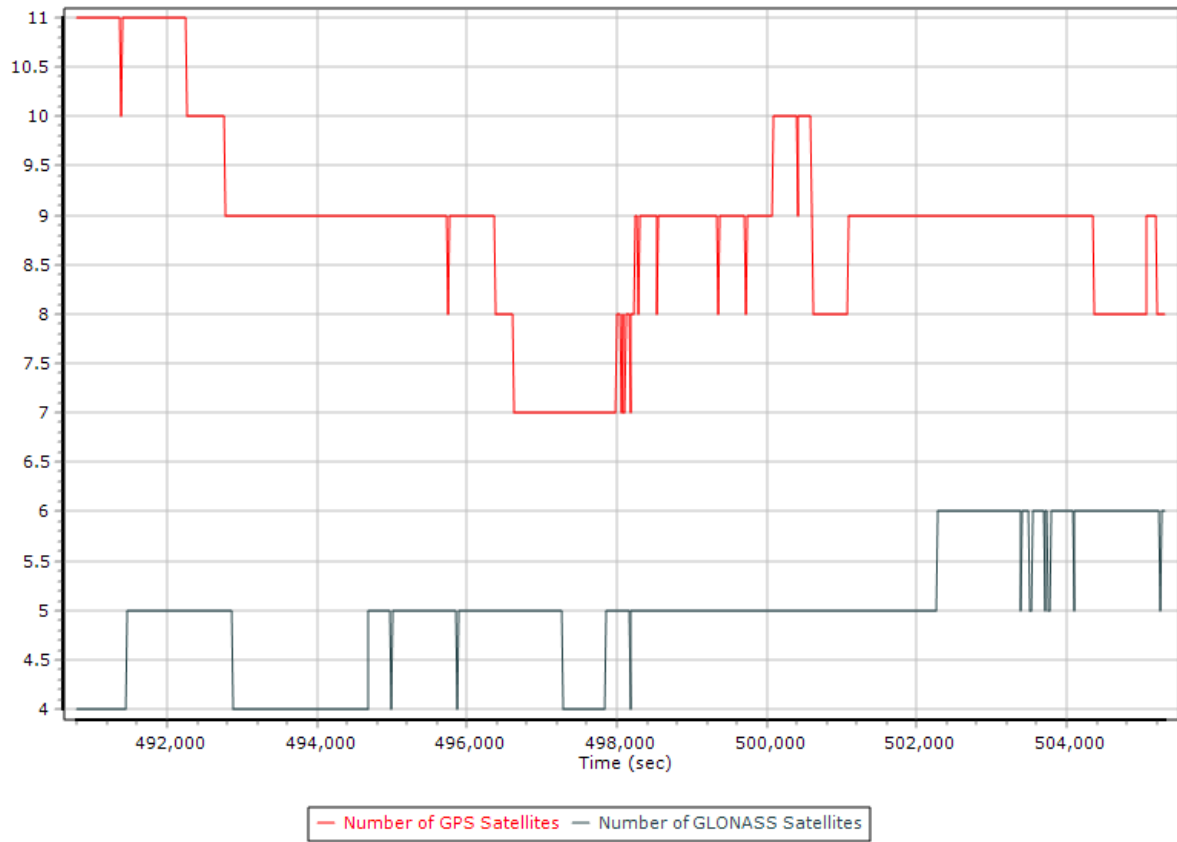
Y:

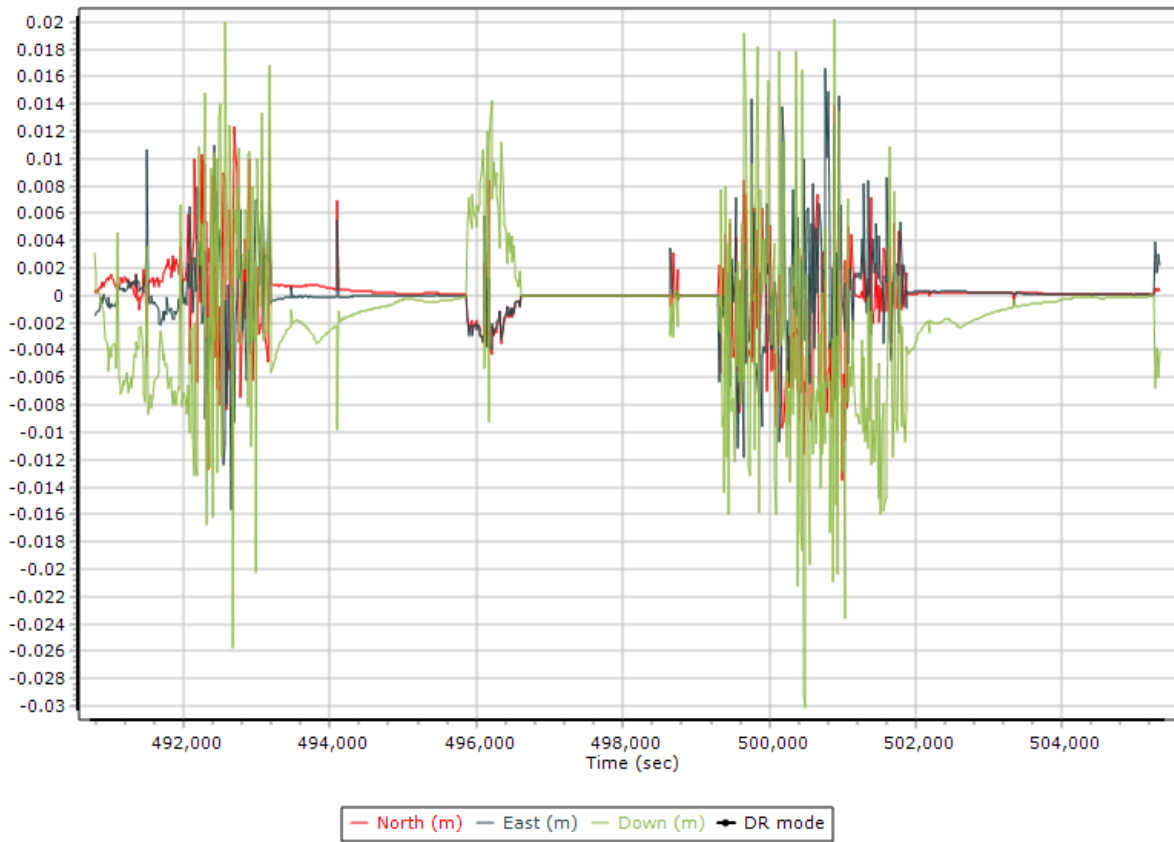
Z:

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: 490109.000
 End: 505339.000
 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

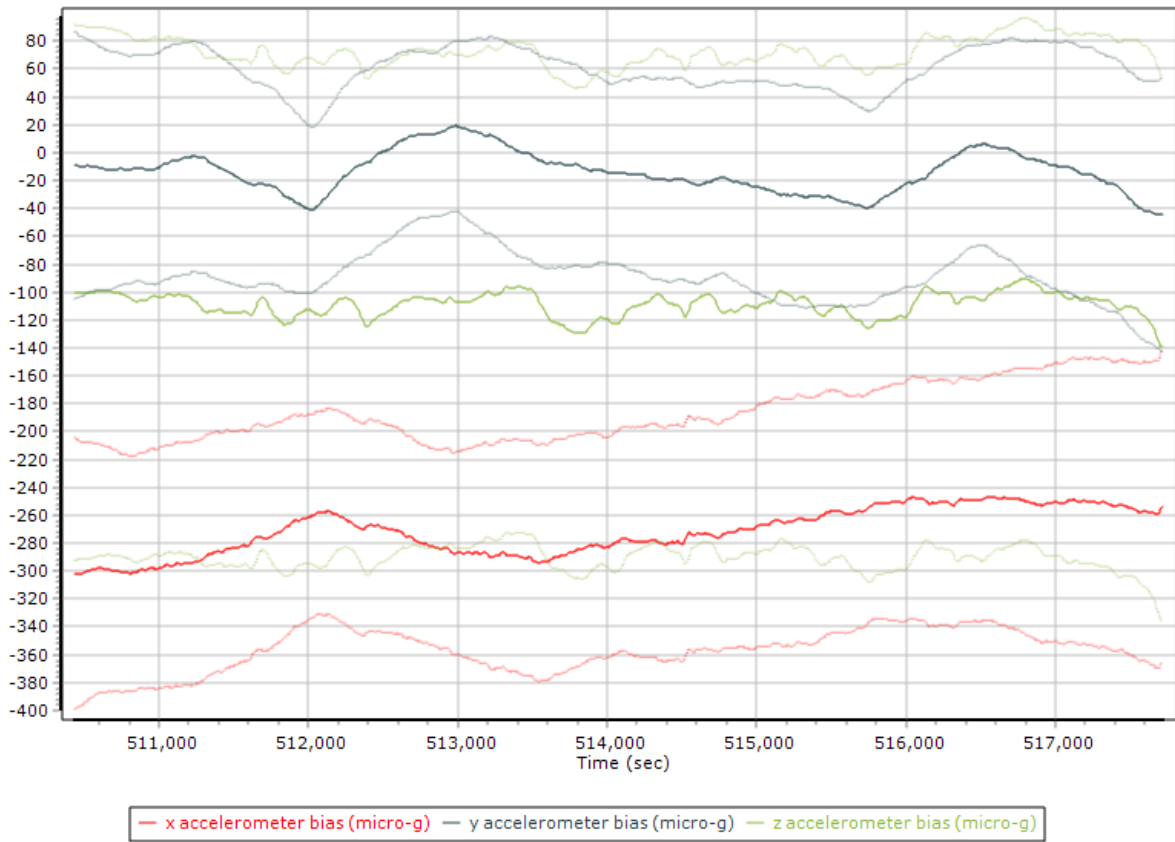
Processable Time Windows

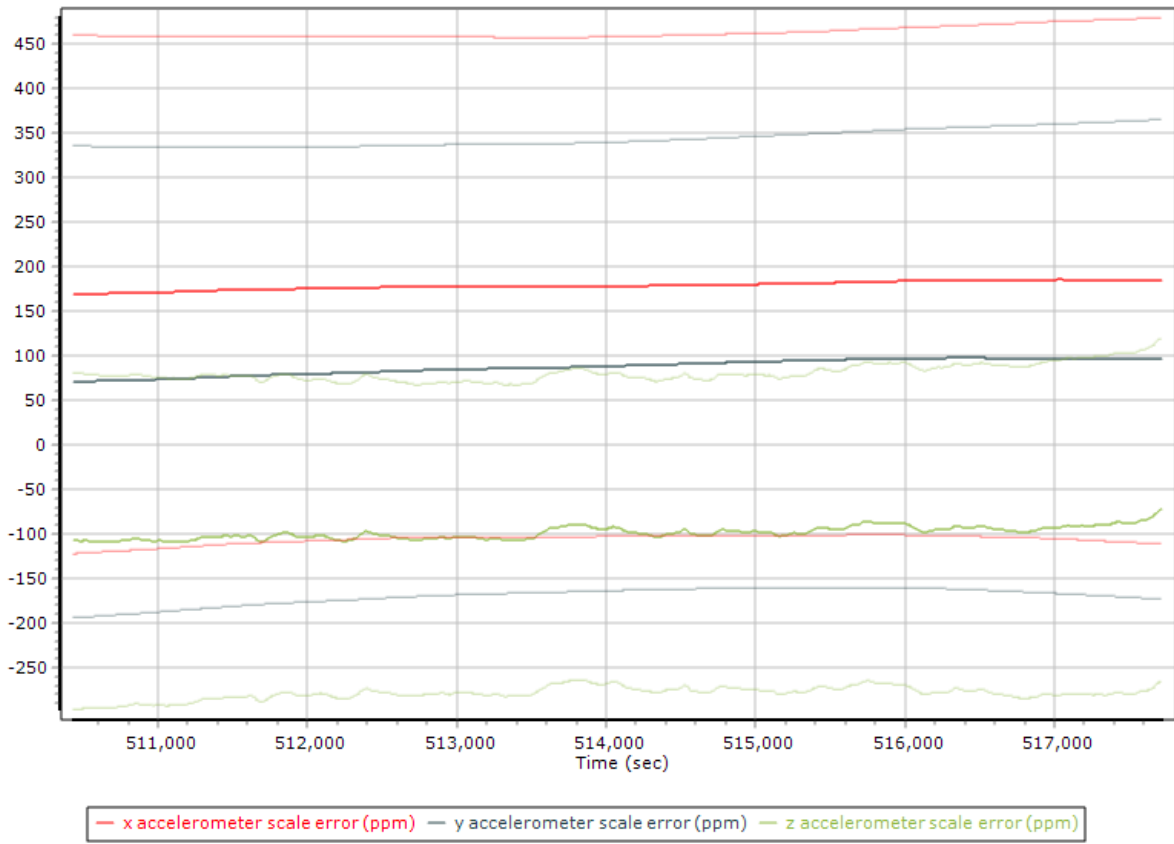
Start after launch Wait Time: 4.000 sec

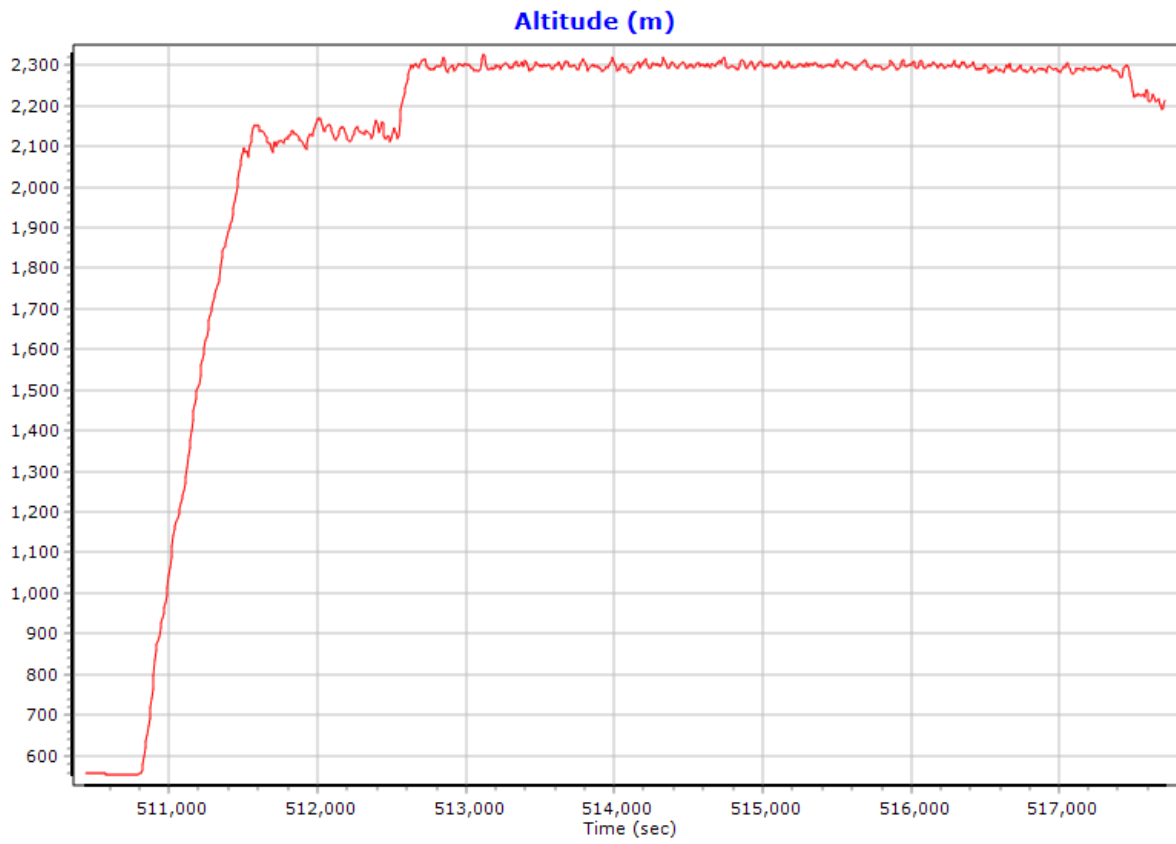
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	490109.000	505339.000	15230.000	End of file

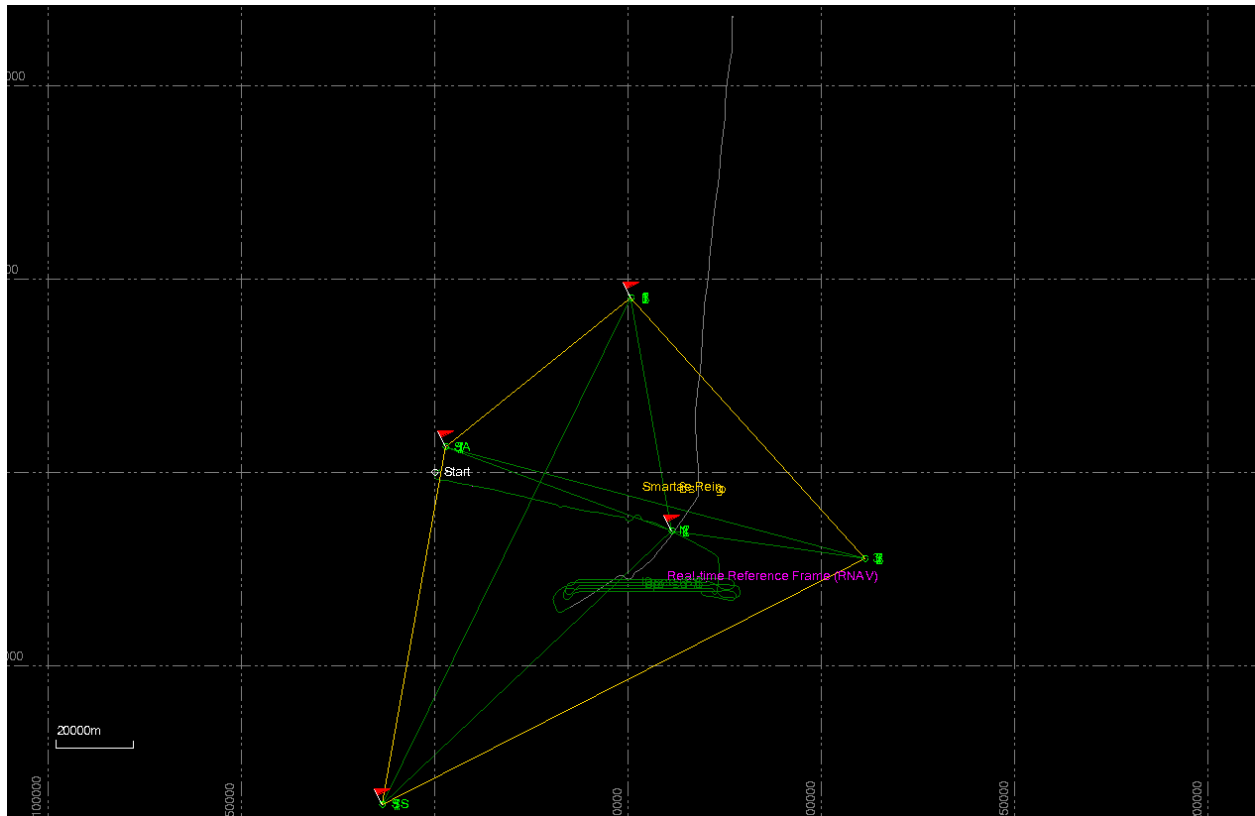
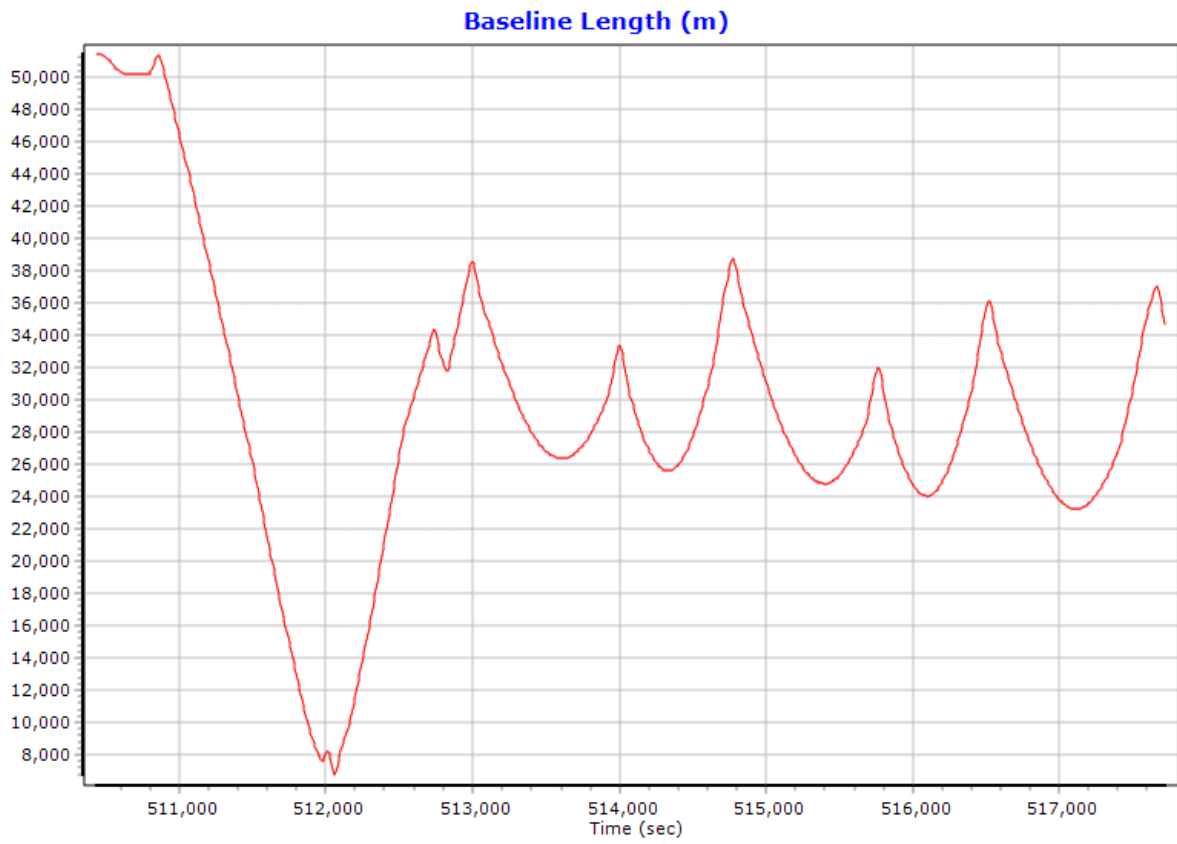
OK Cancel

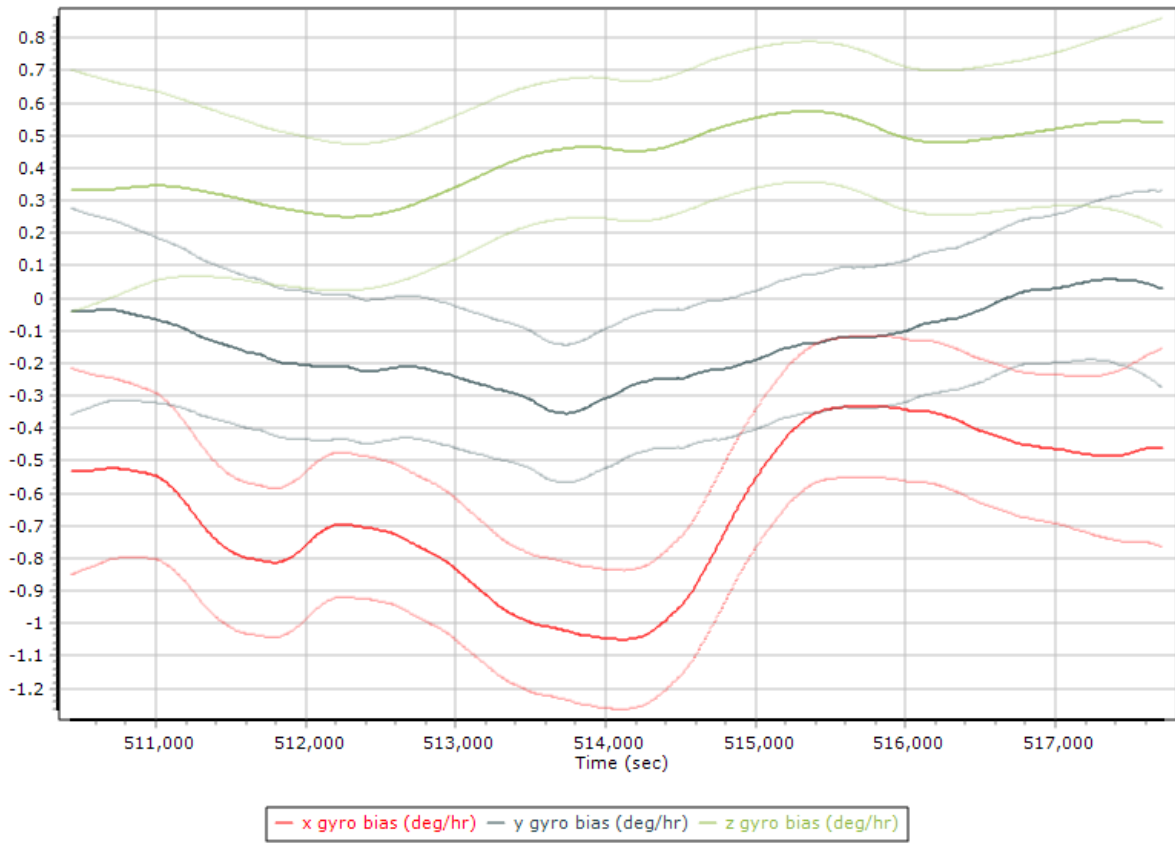
CAU18061B

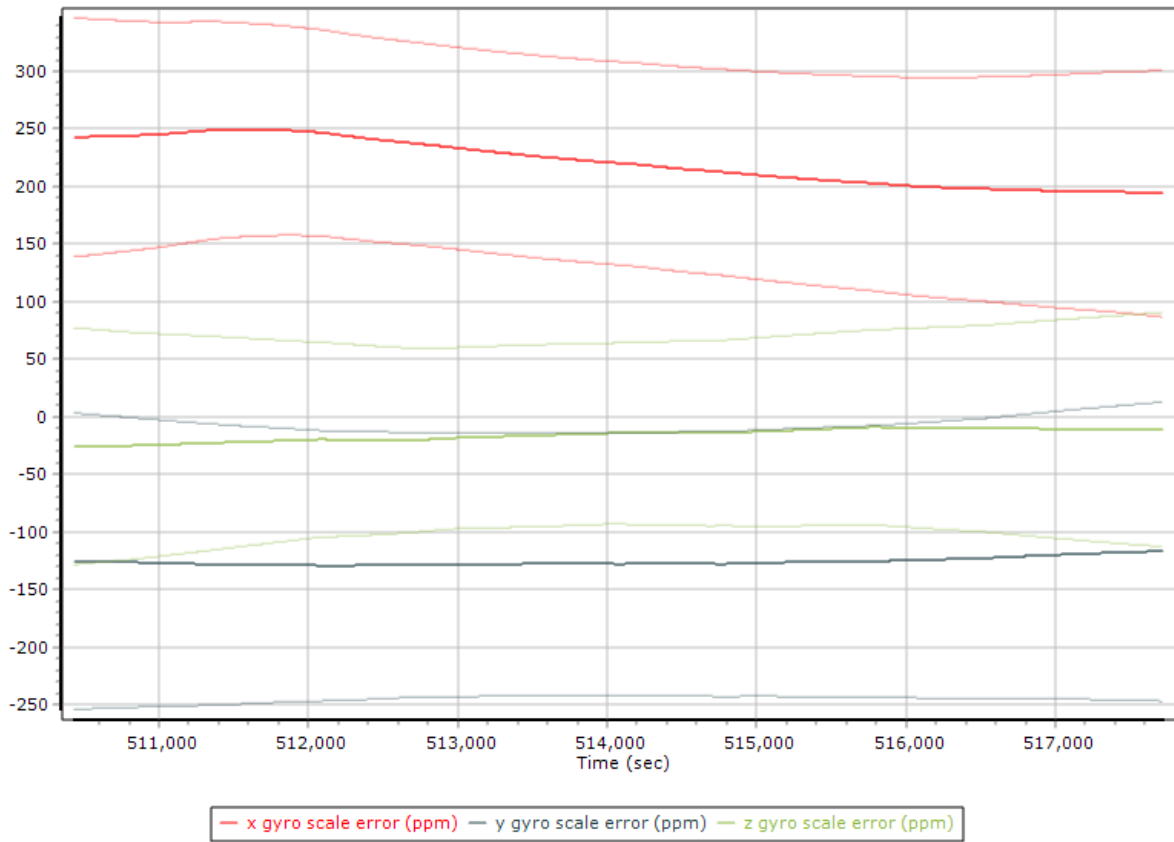












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation

<3cm 10cm 50cm 1m 10m

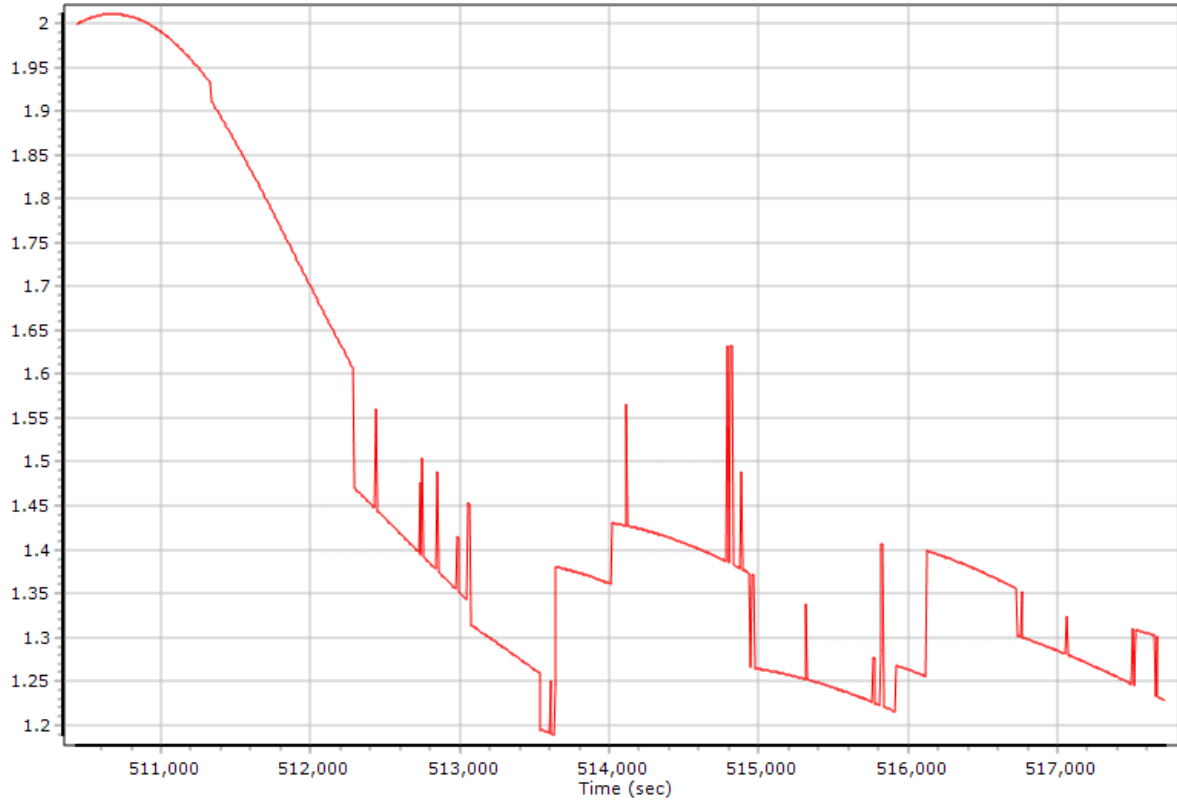
Aircraft to Reference Mounting Angles

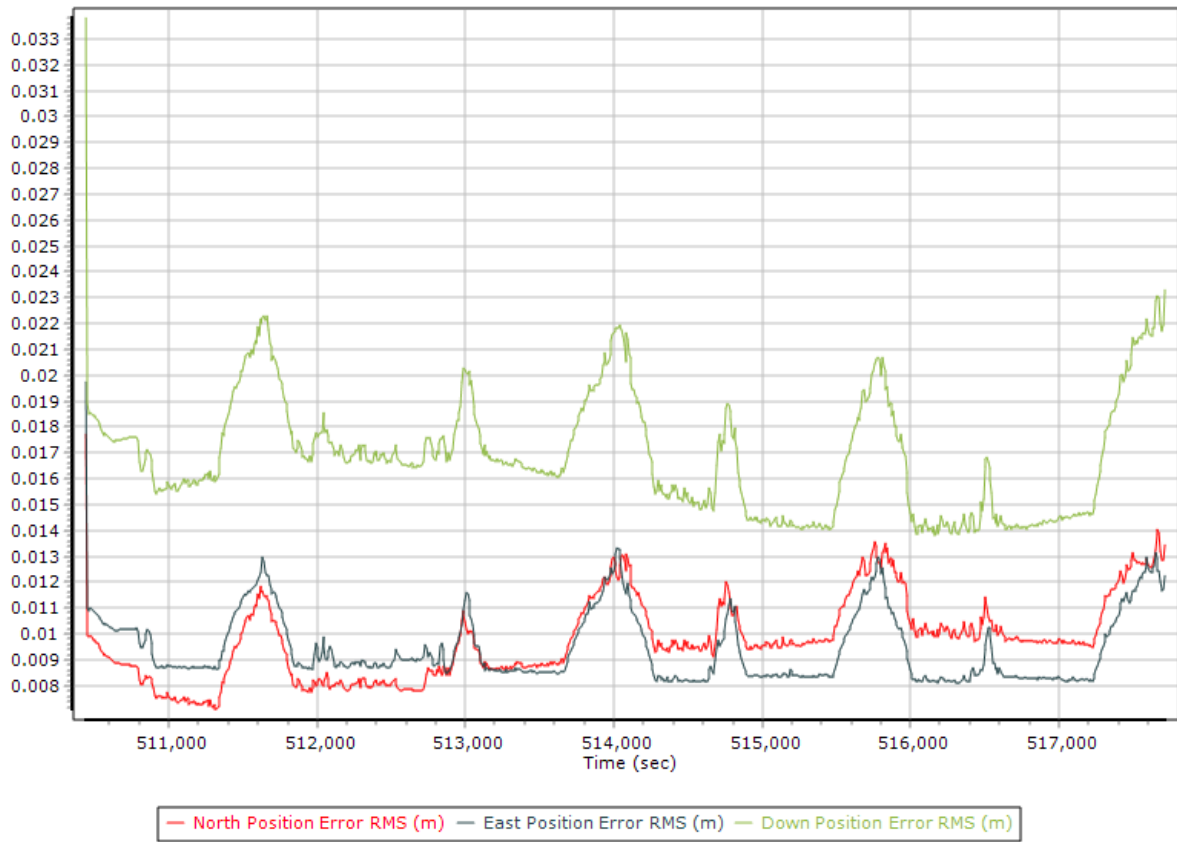
X:

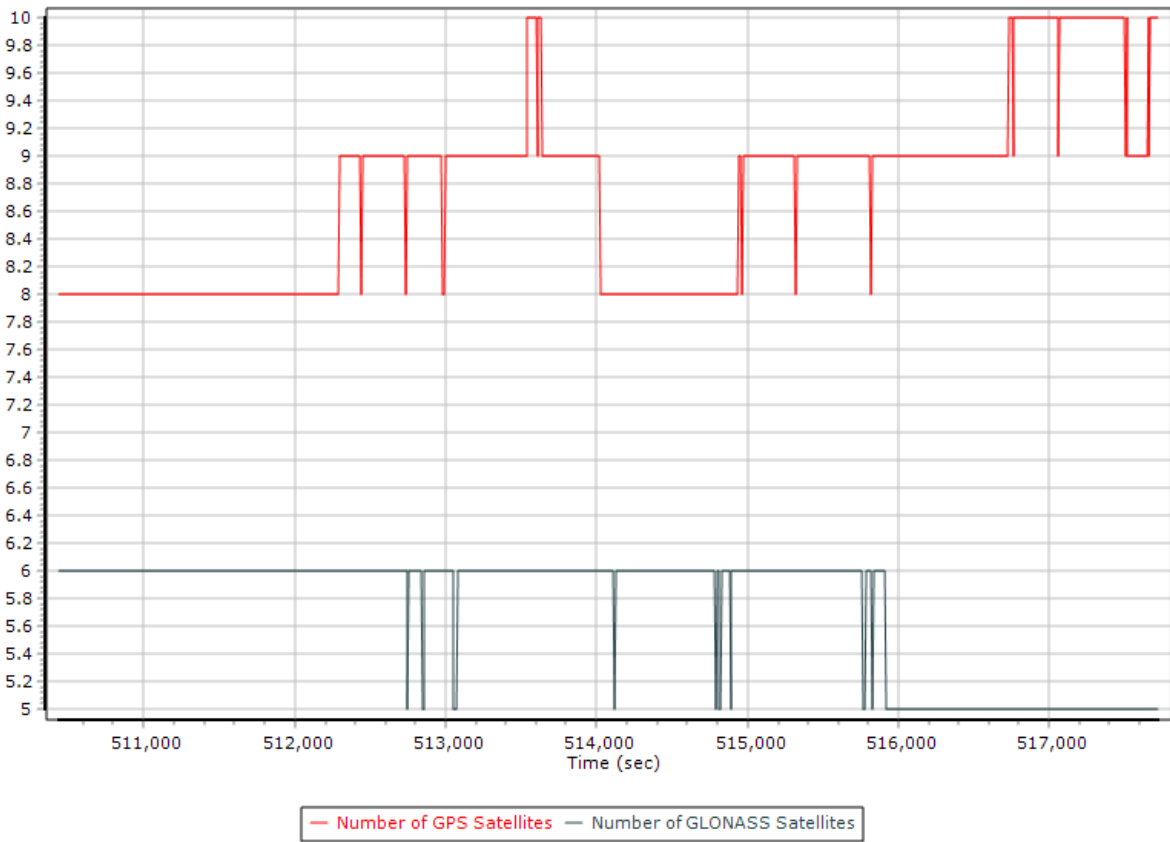
Y:

Z:

PDOP









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: 509930.000
 End: 520693.000
 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

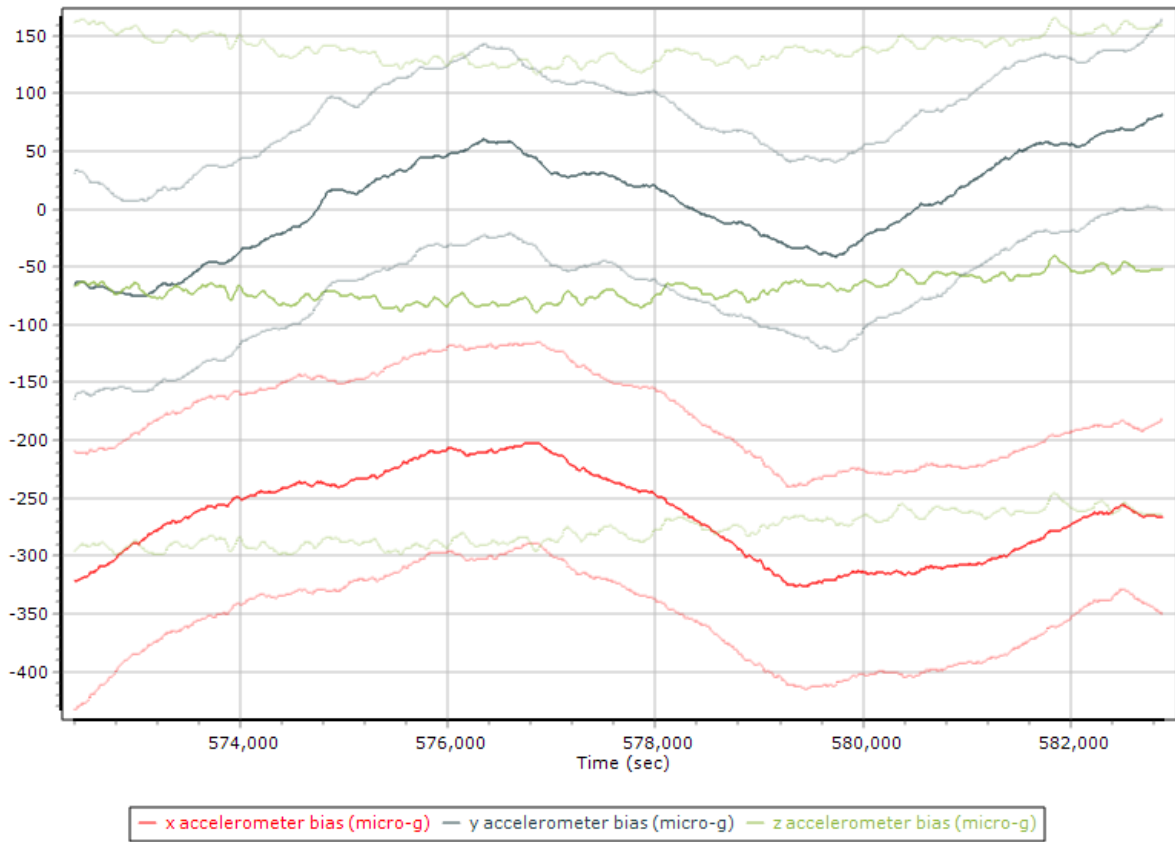
Processable Time Windows

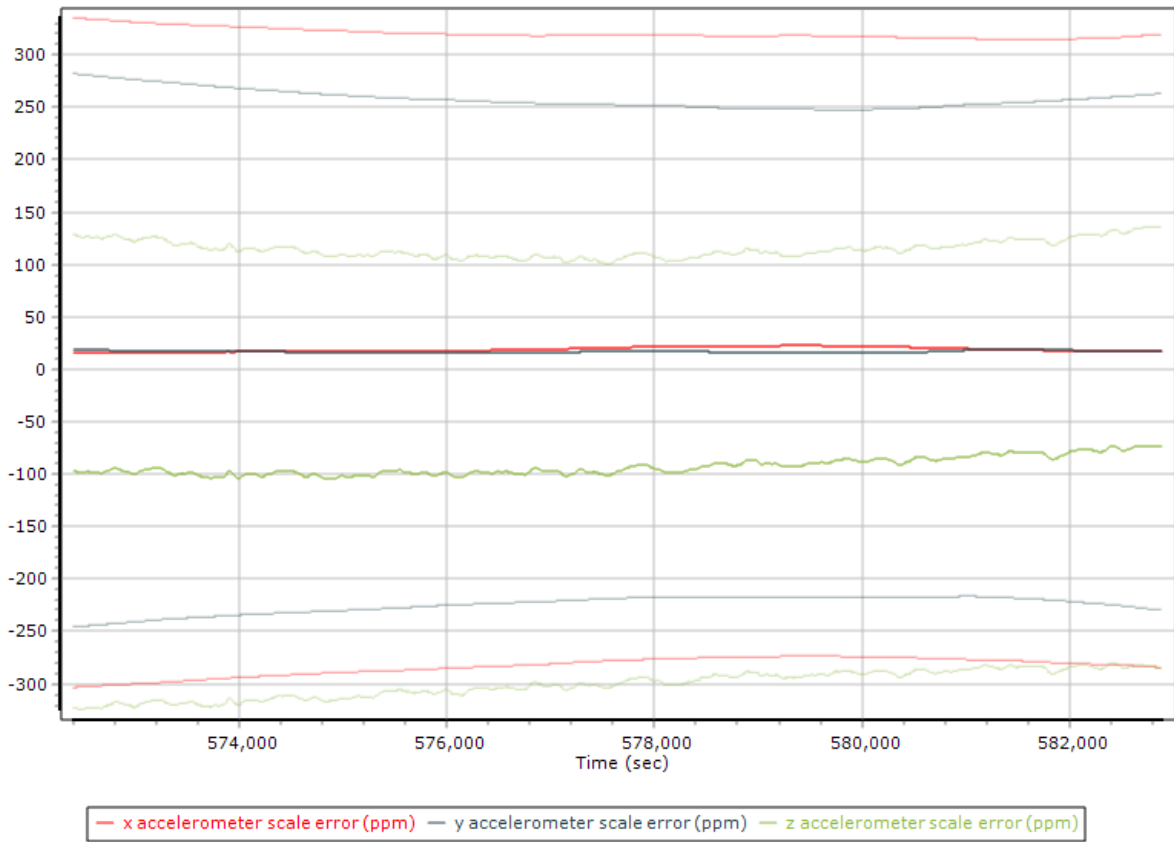
Start after launch Wait Time: 4.000 sec

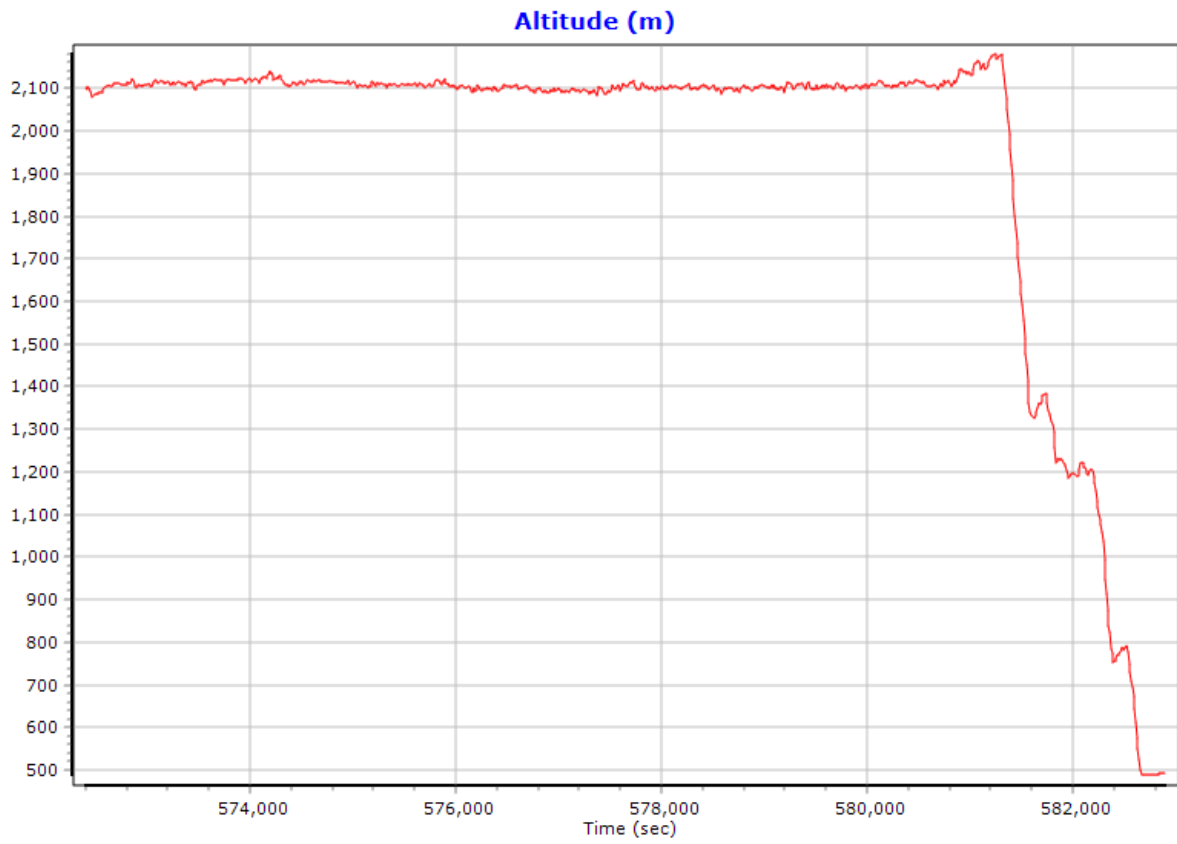
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	509930.000	520693.000	10763.000	End of file

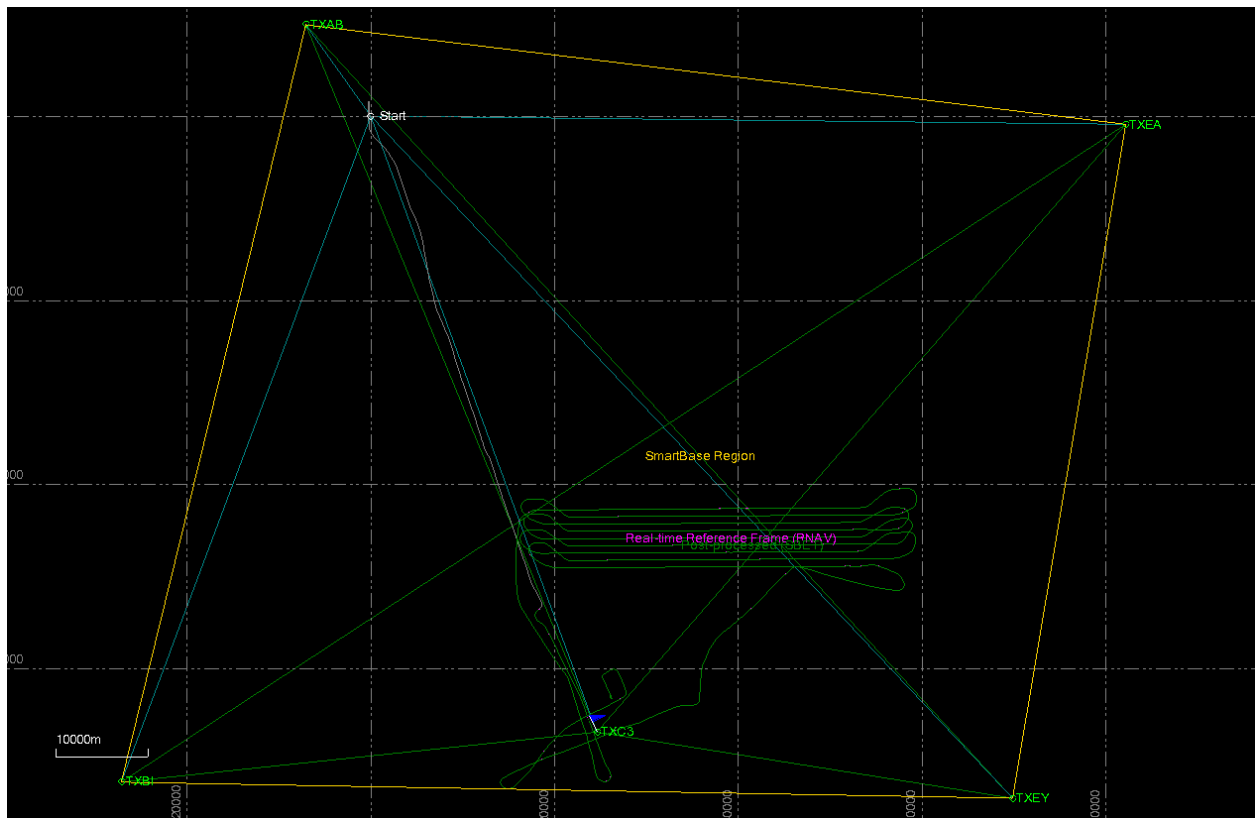
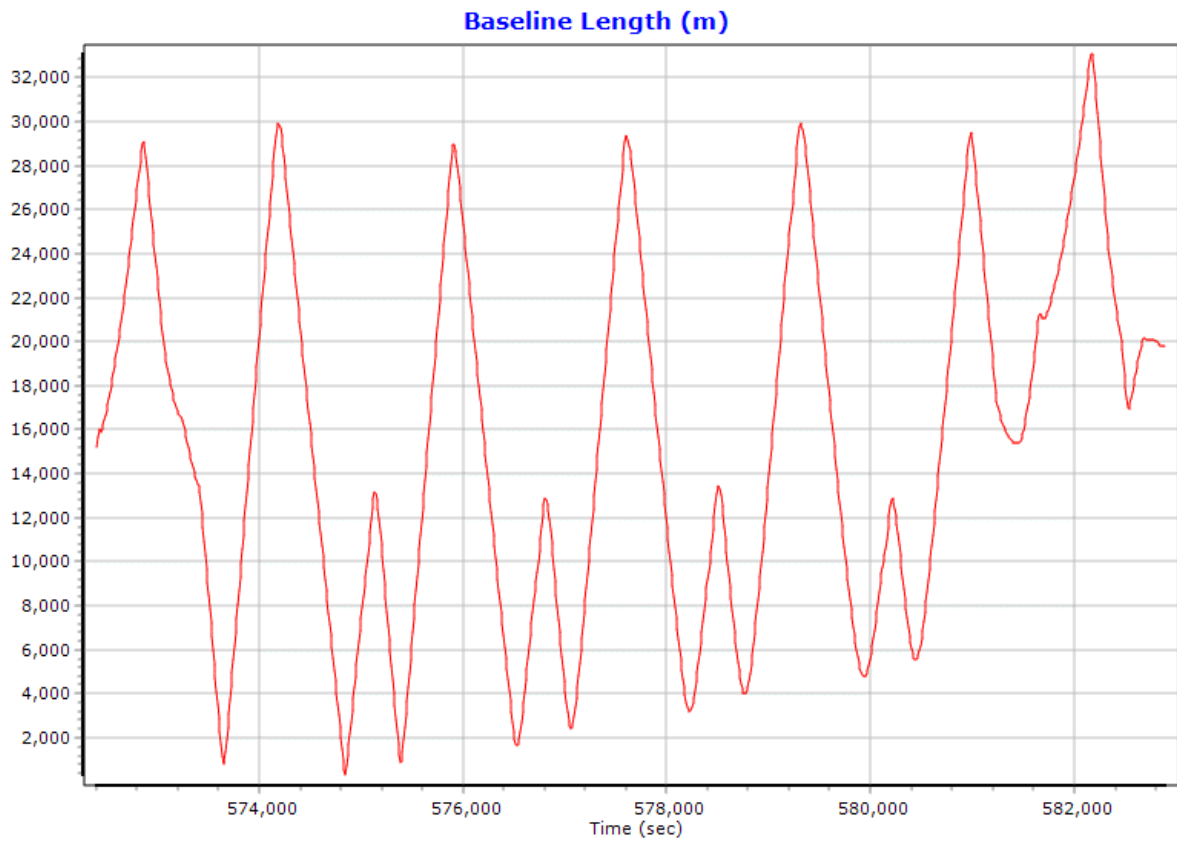
OK Cancel

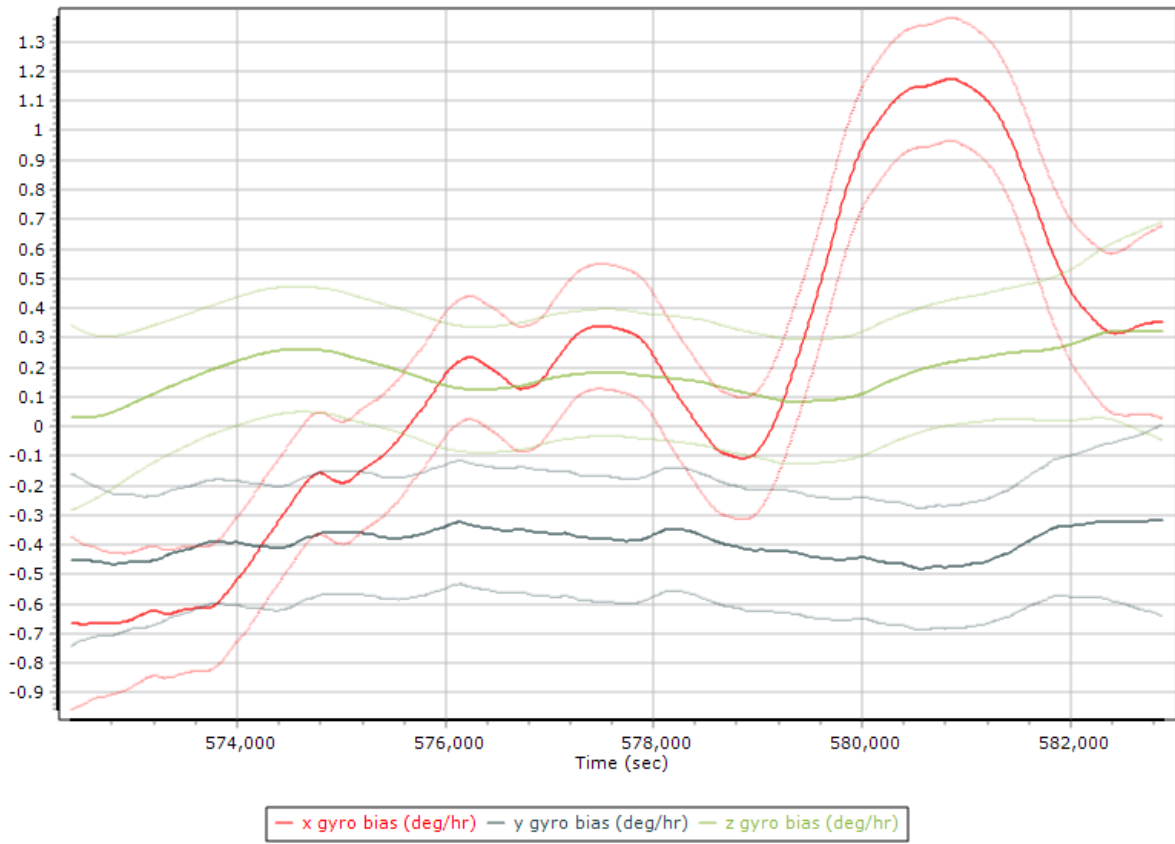
CAU18062A

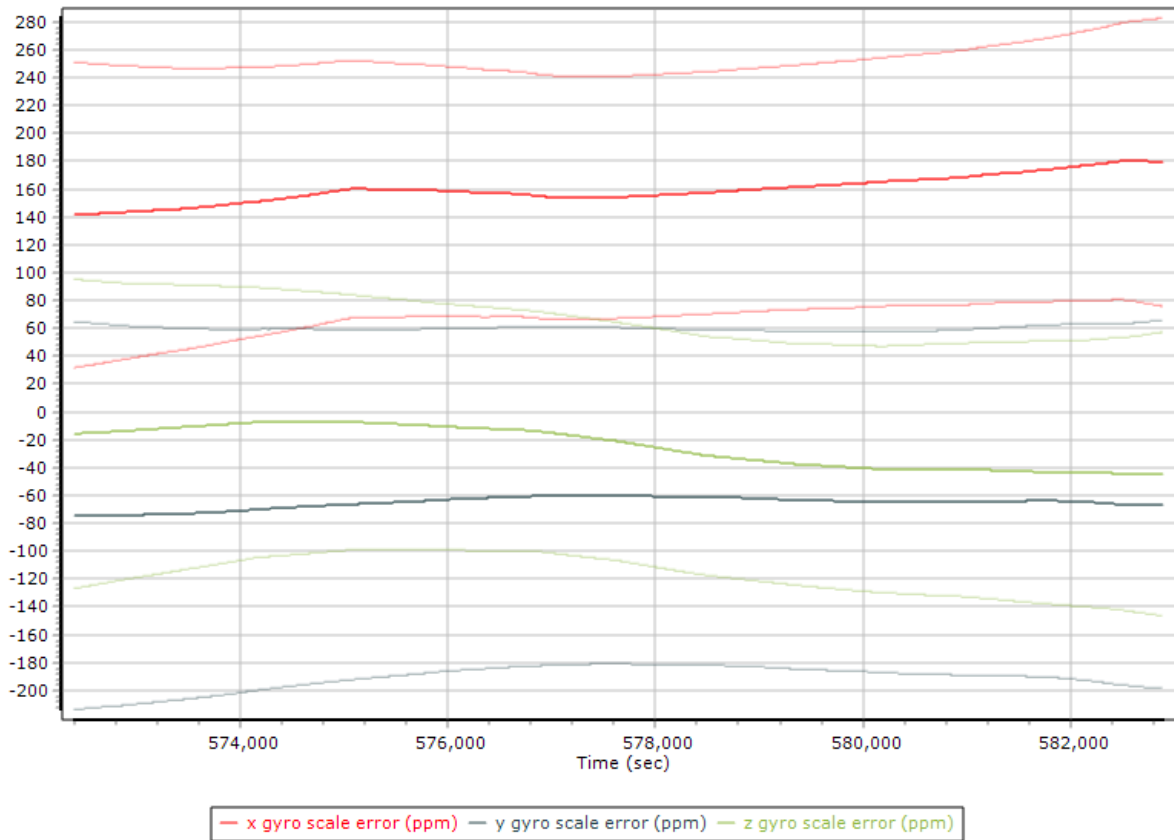












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

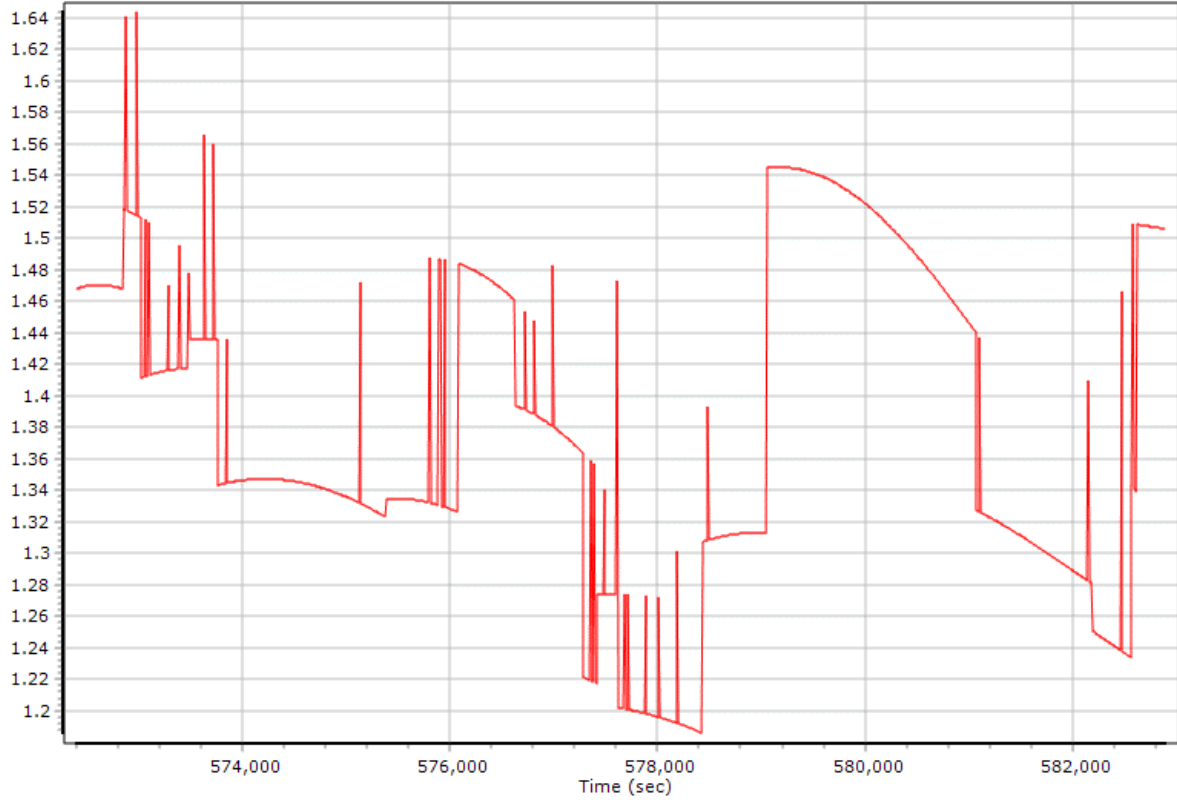
Aircraft to Reference Mounting Angles

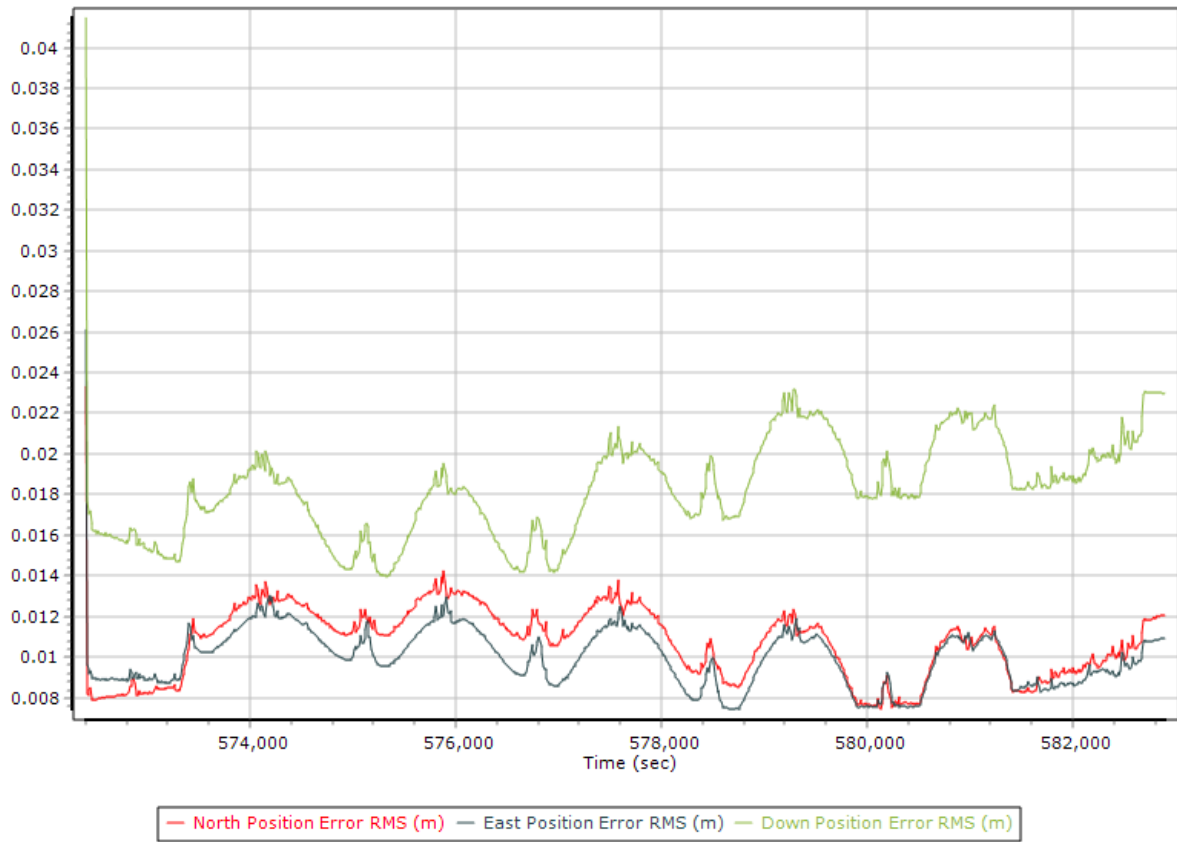
X:

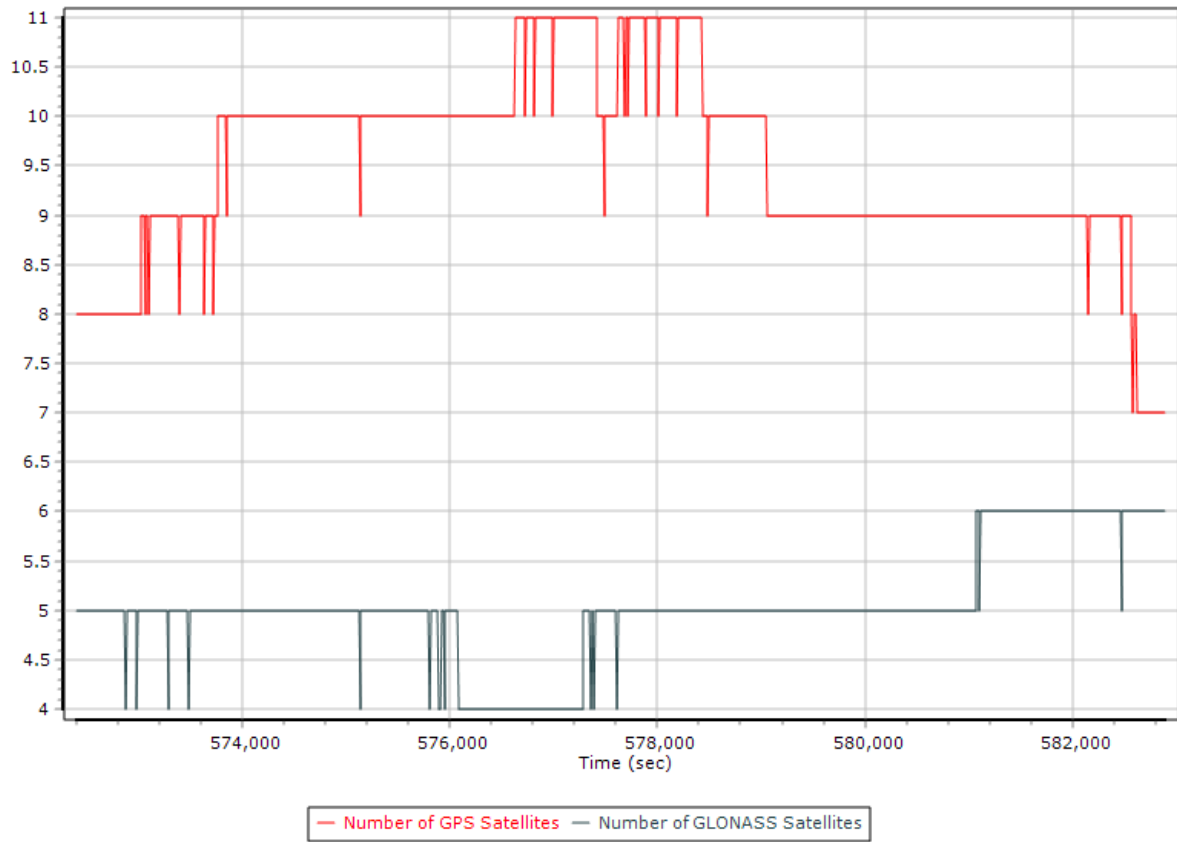
Y:

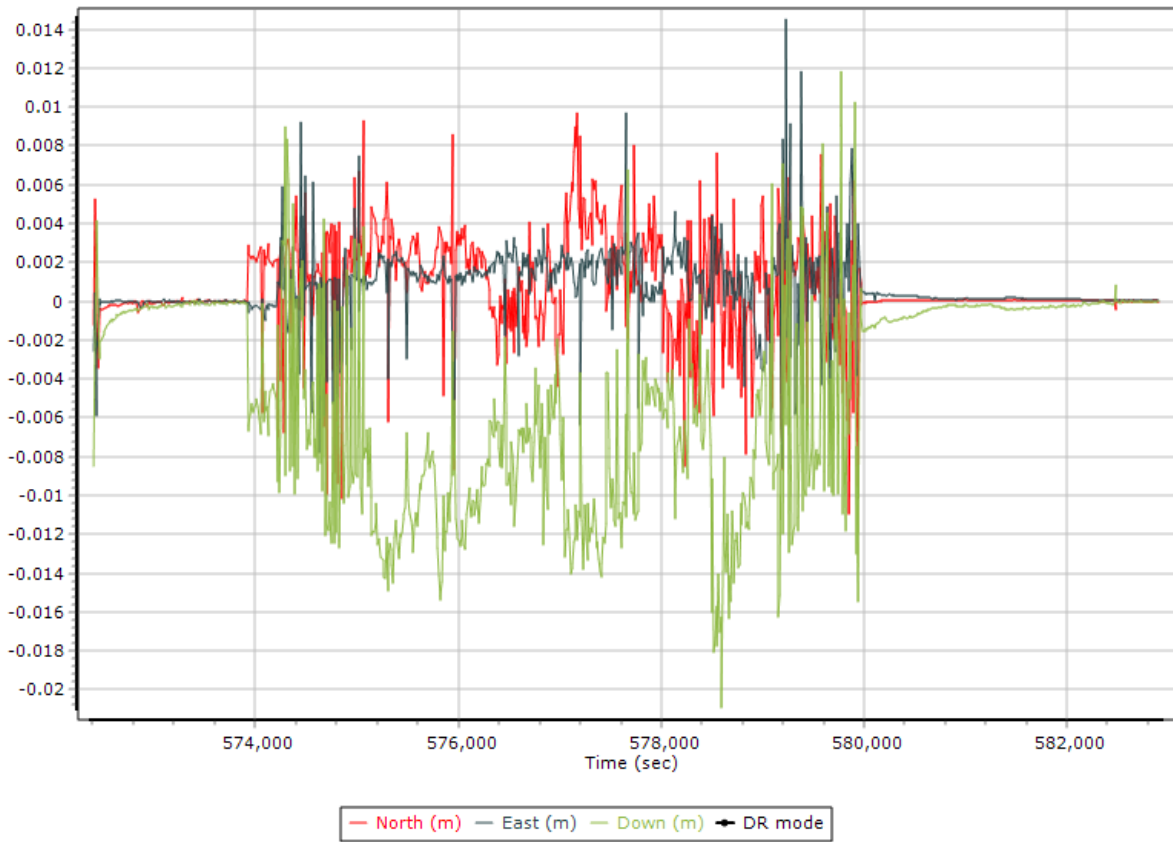
Z:

PDOP









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: 570044.020
 End: 582906.000
 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

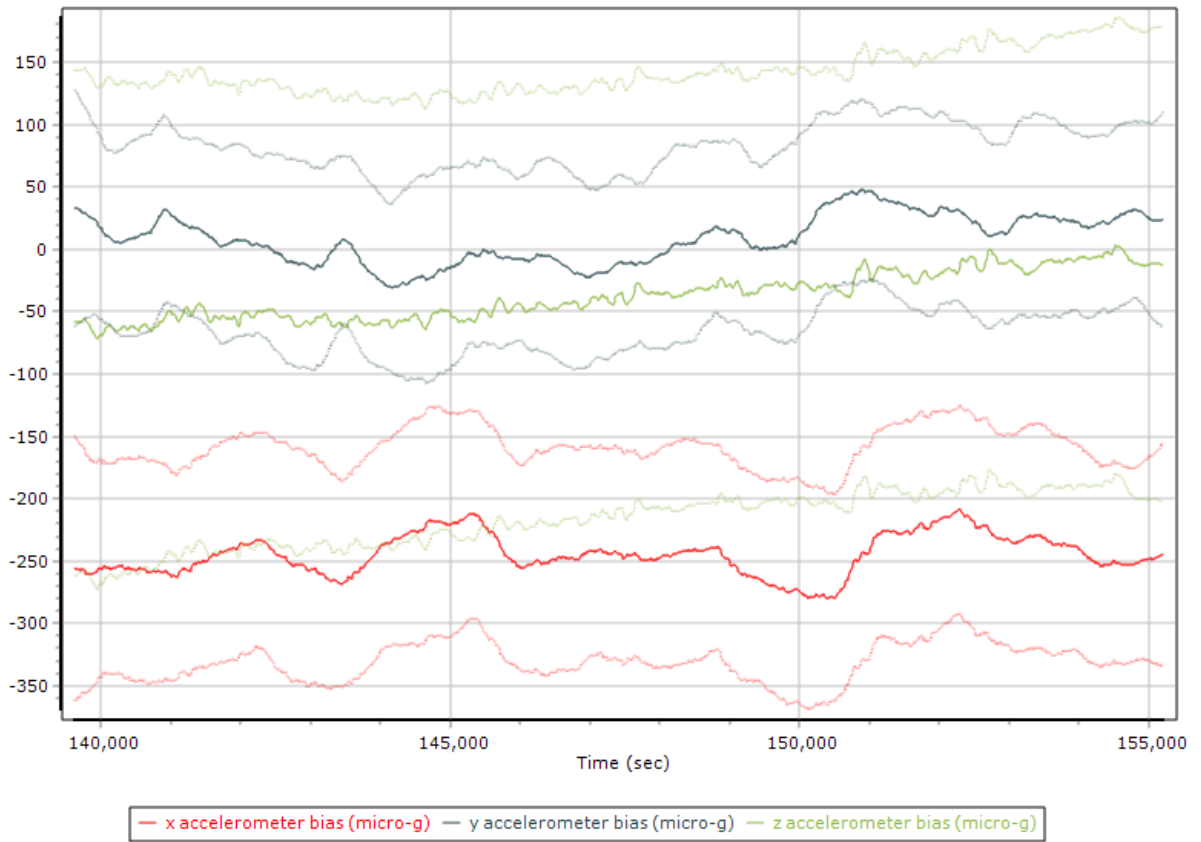
Processable Time Windows

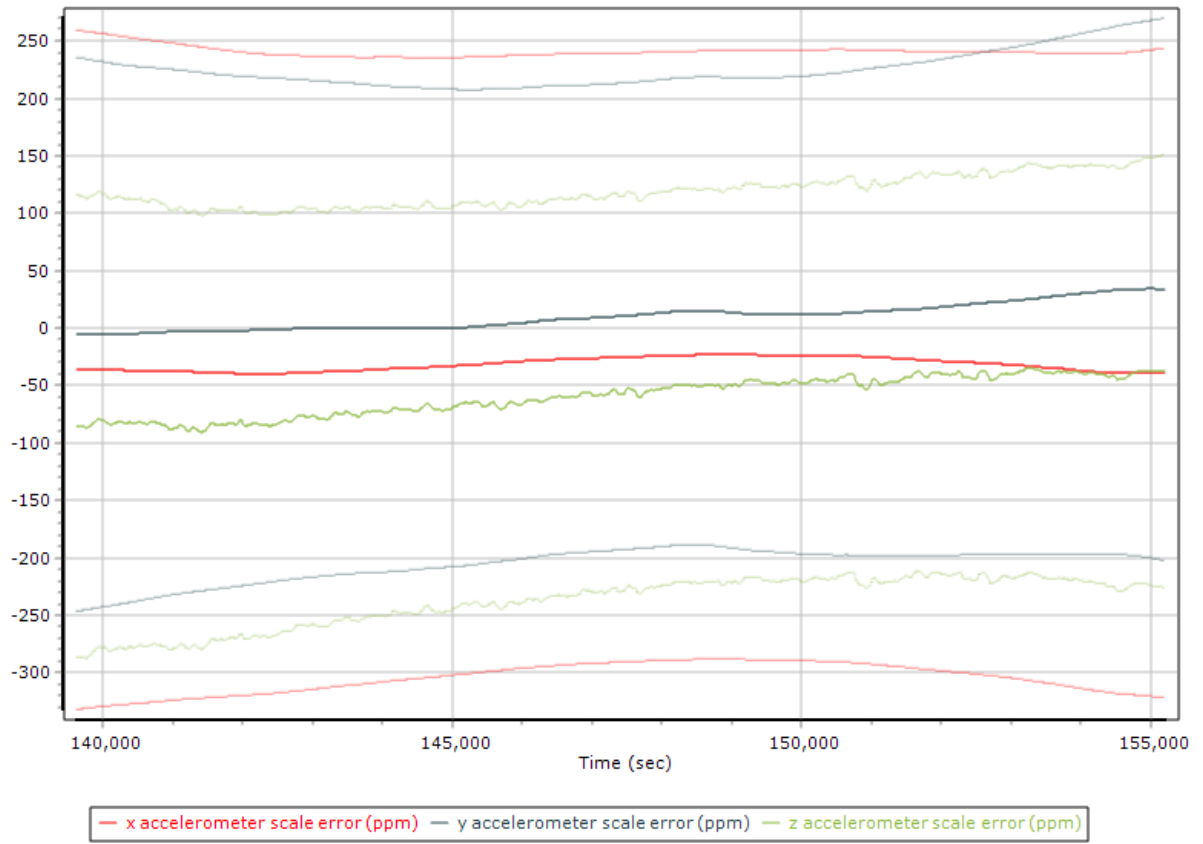
Start after launch Wait Time: 4.000 sec

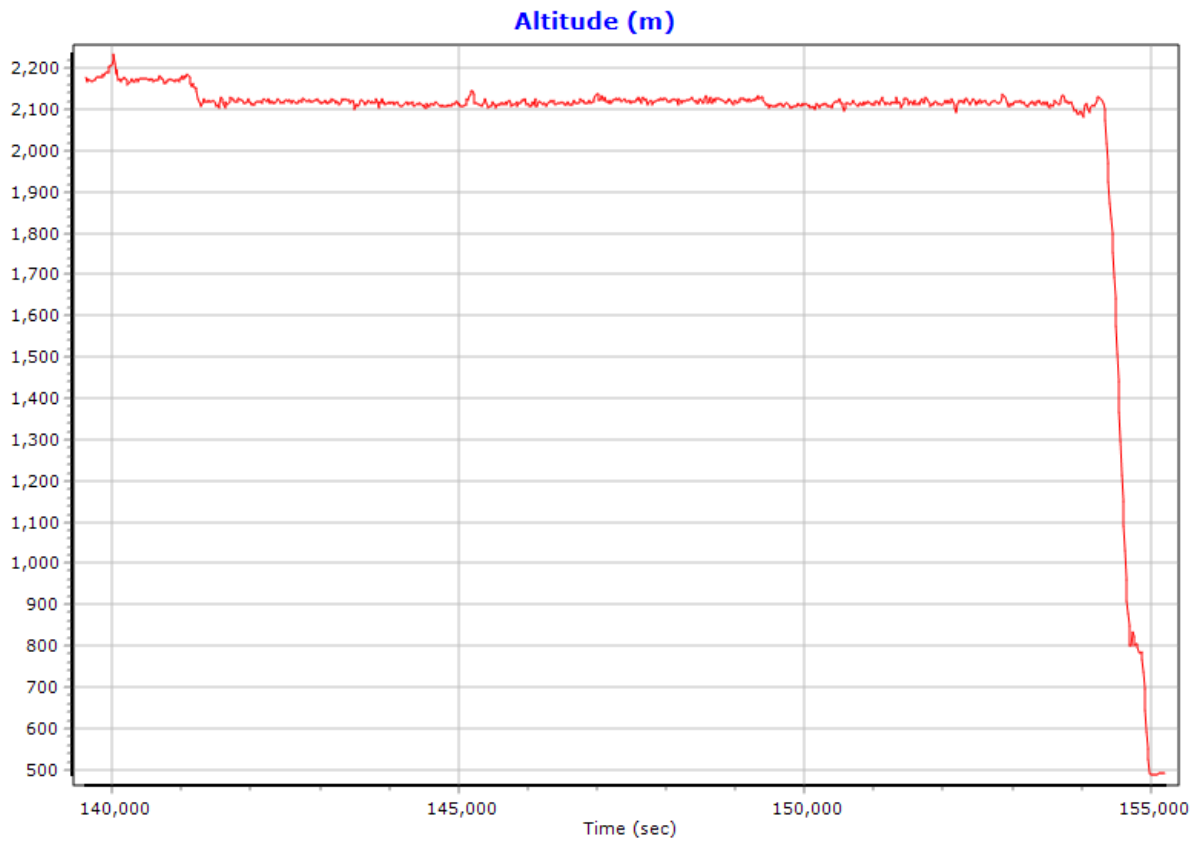
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	570044.020	582906.000	12861.980	End of file

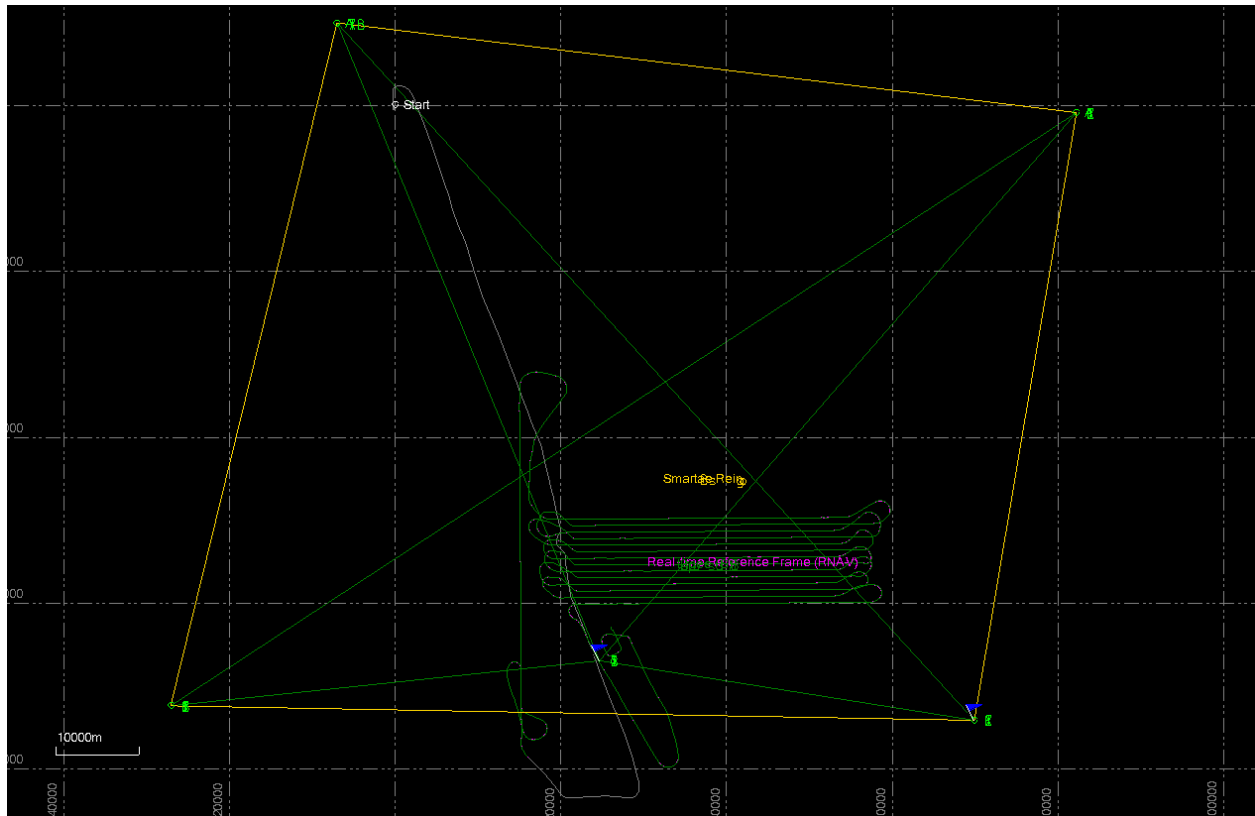
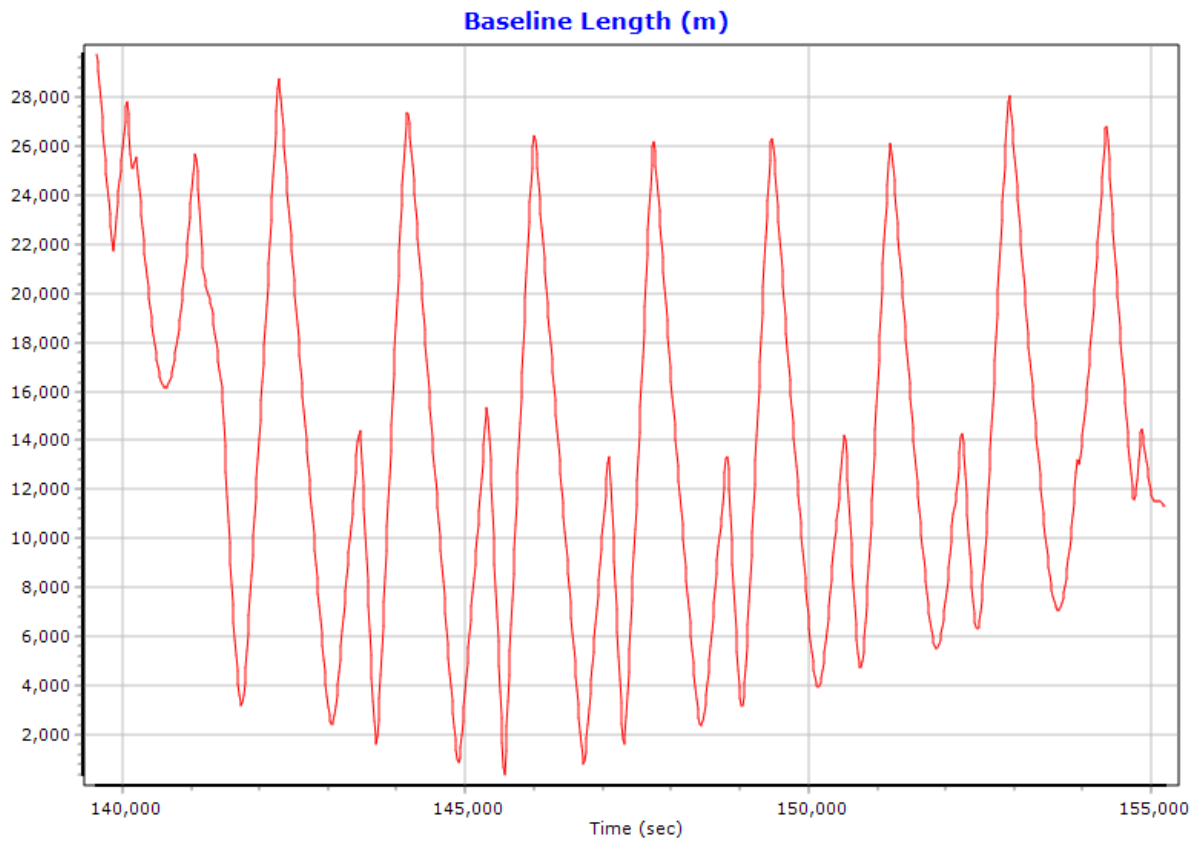
OK Cancel

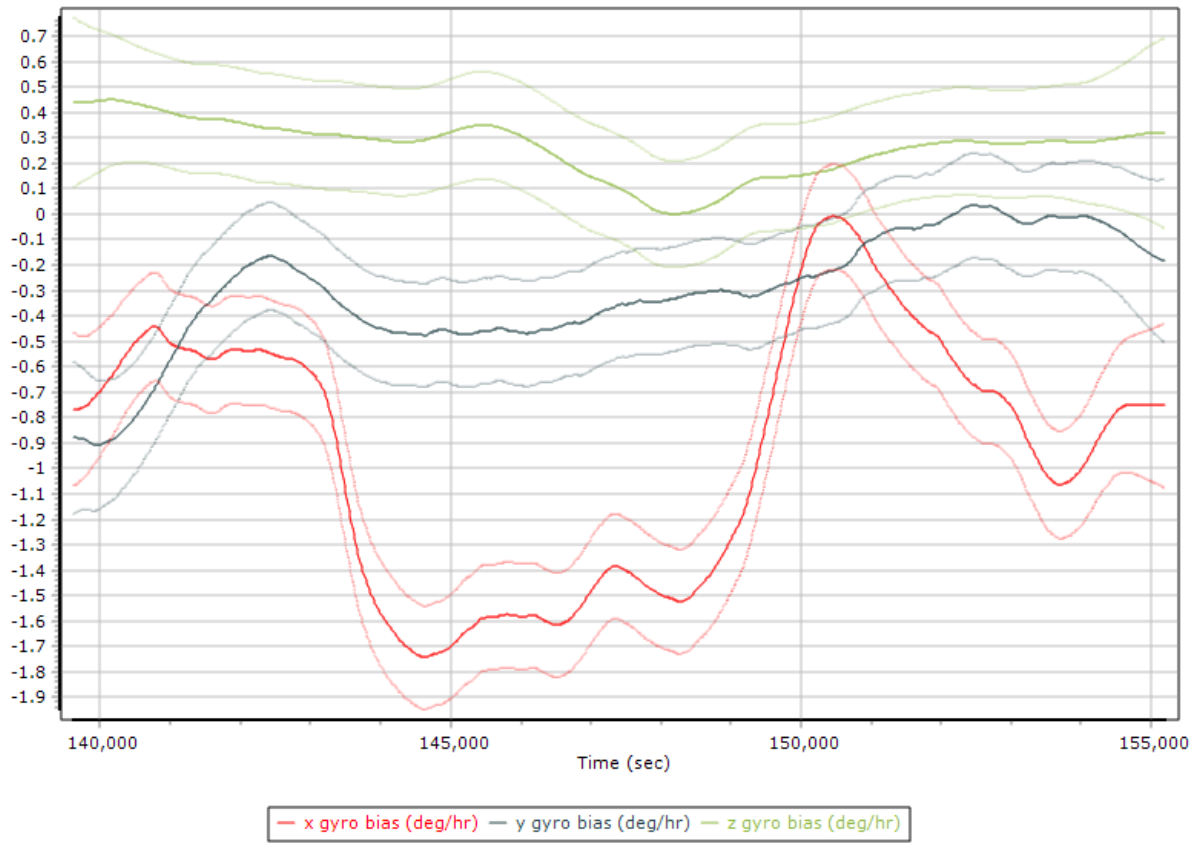
CAU18064A

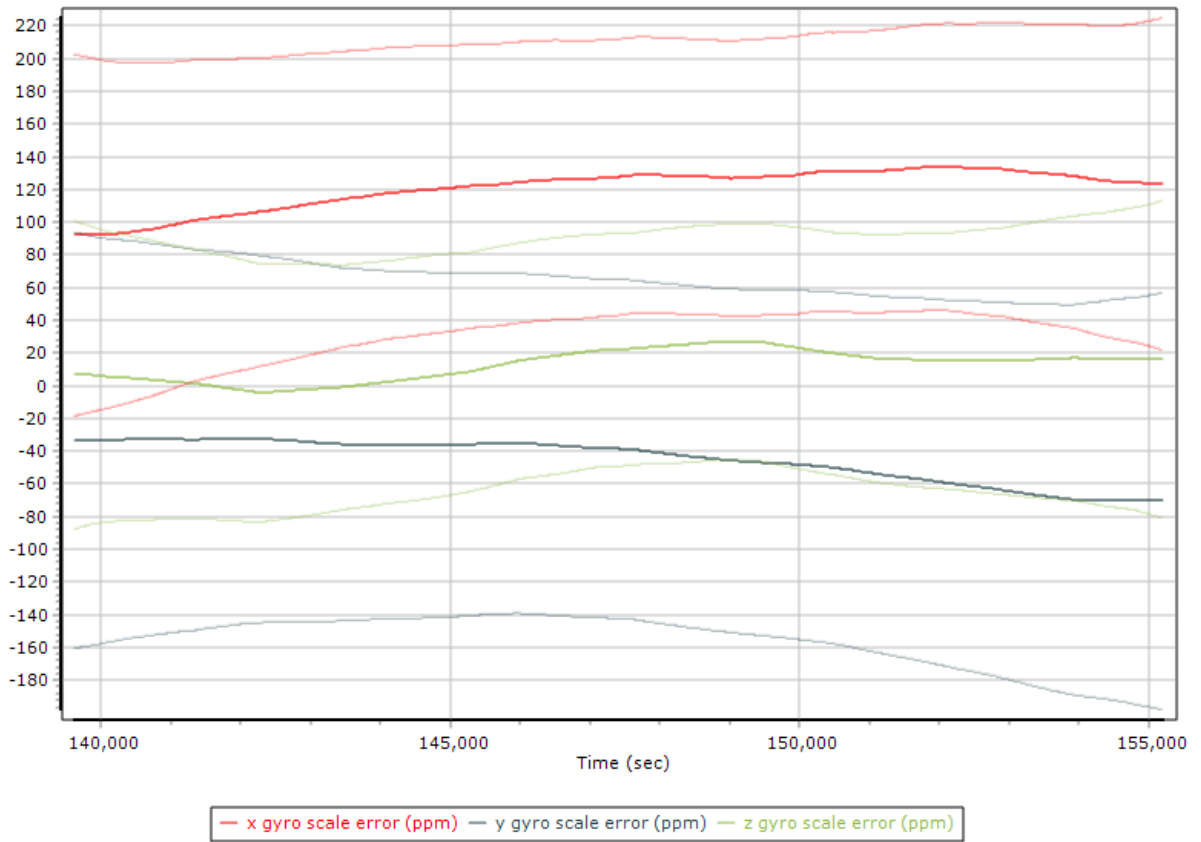












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

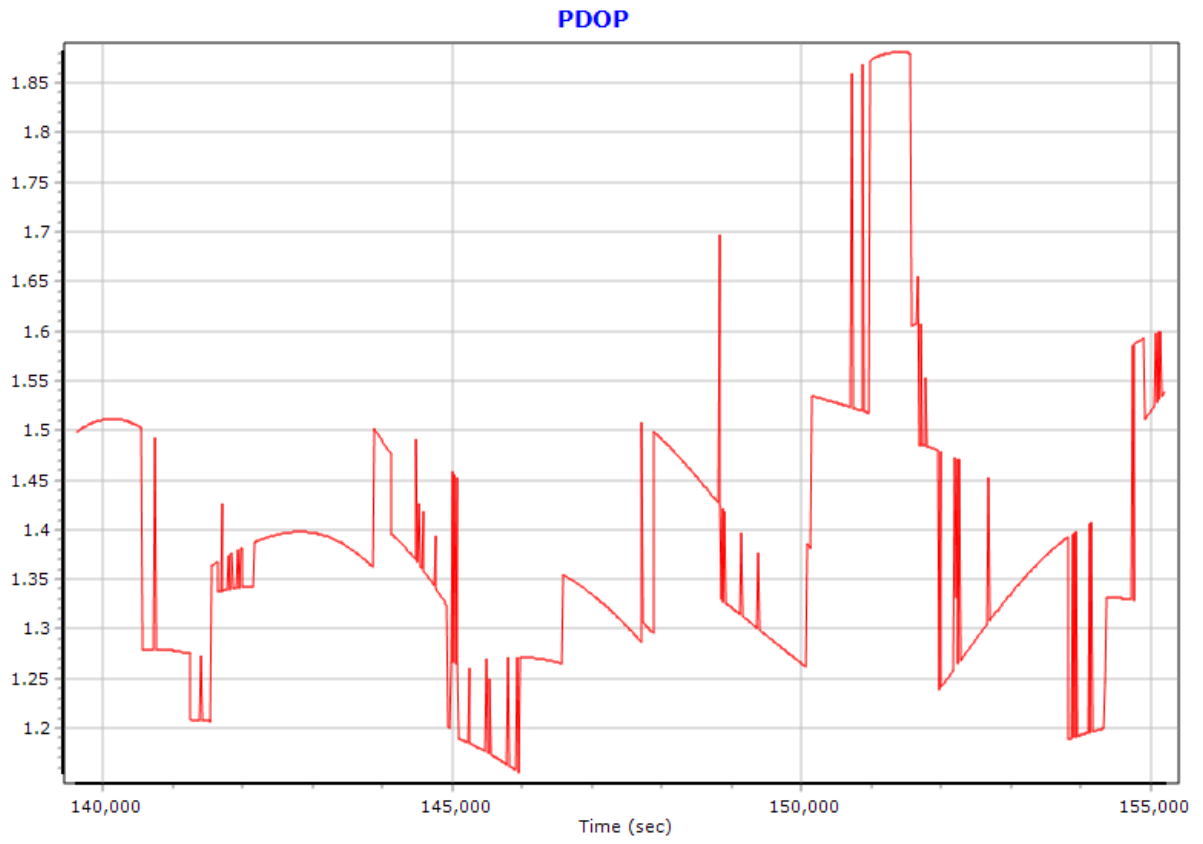
<3cm 10cm 50cm 1m 10m

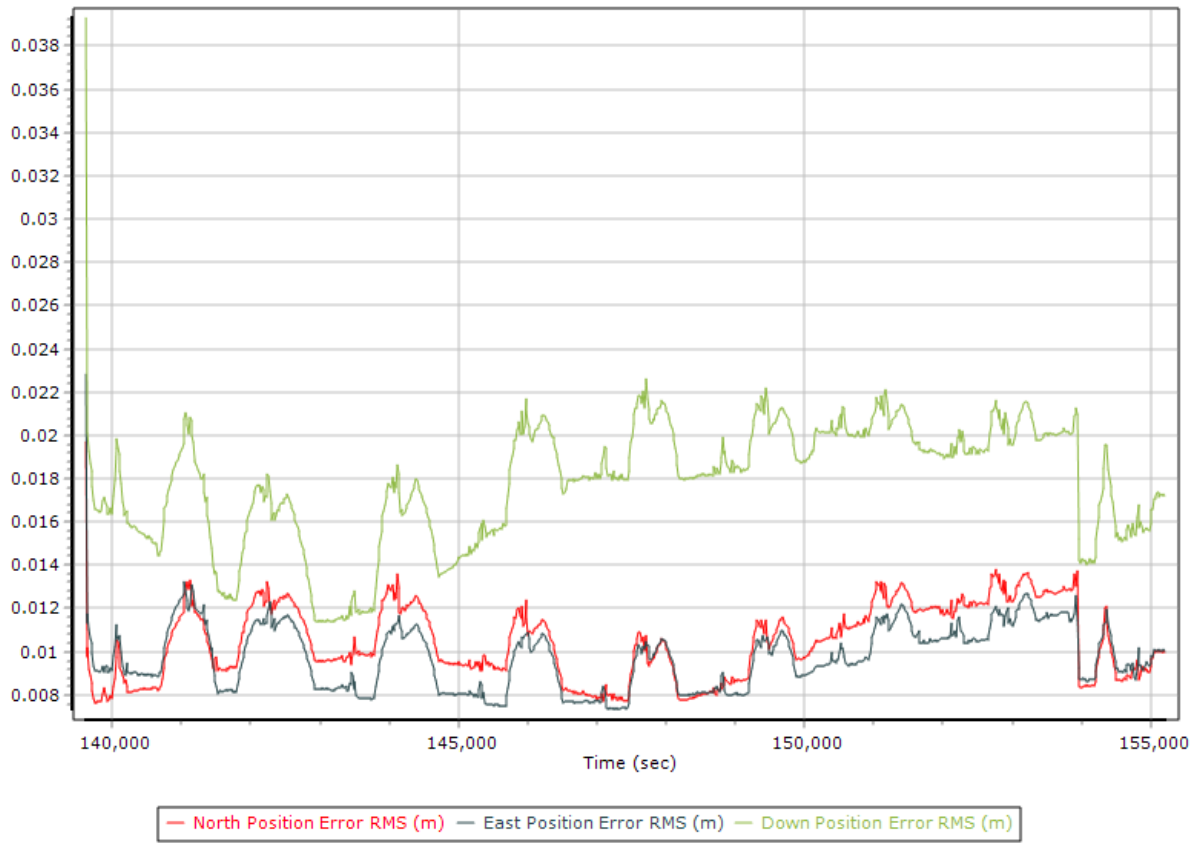
Aircraft to Reference Mounting Angles

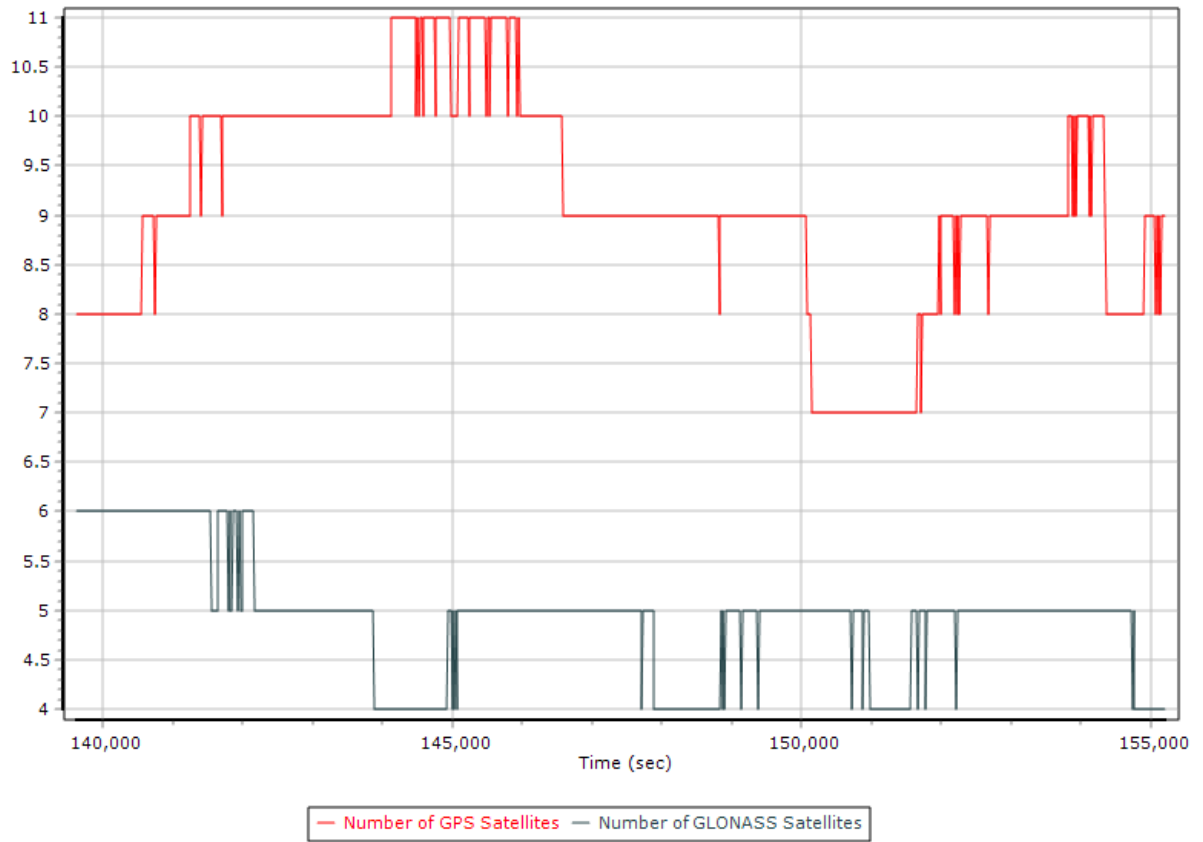
X:

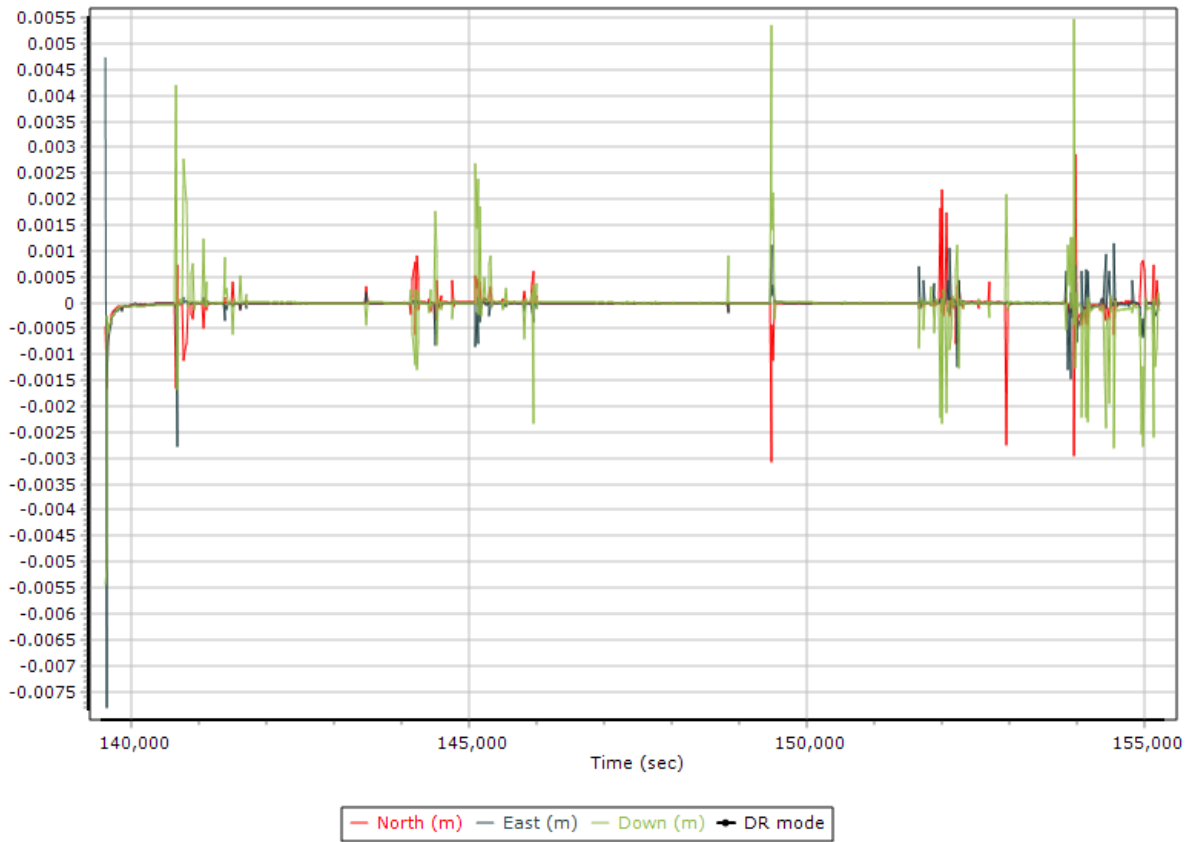
Y:

Z:









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: 136926.000
End: 155232.000

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

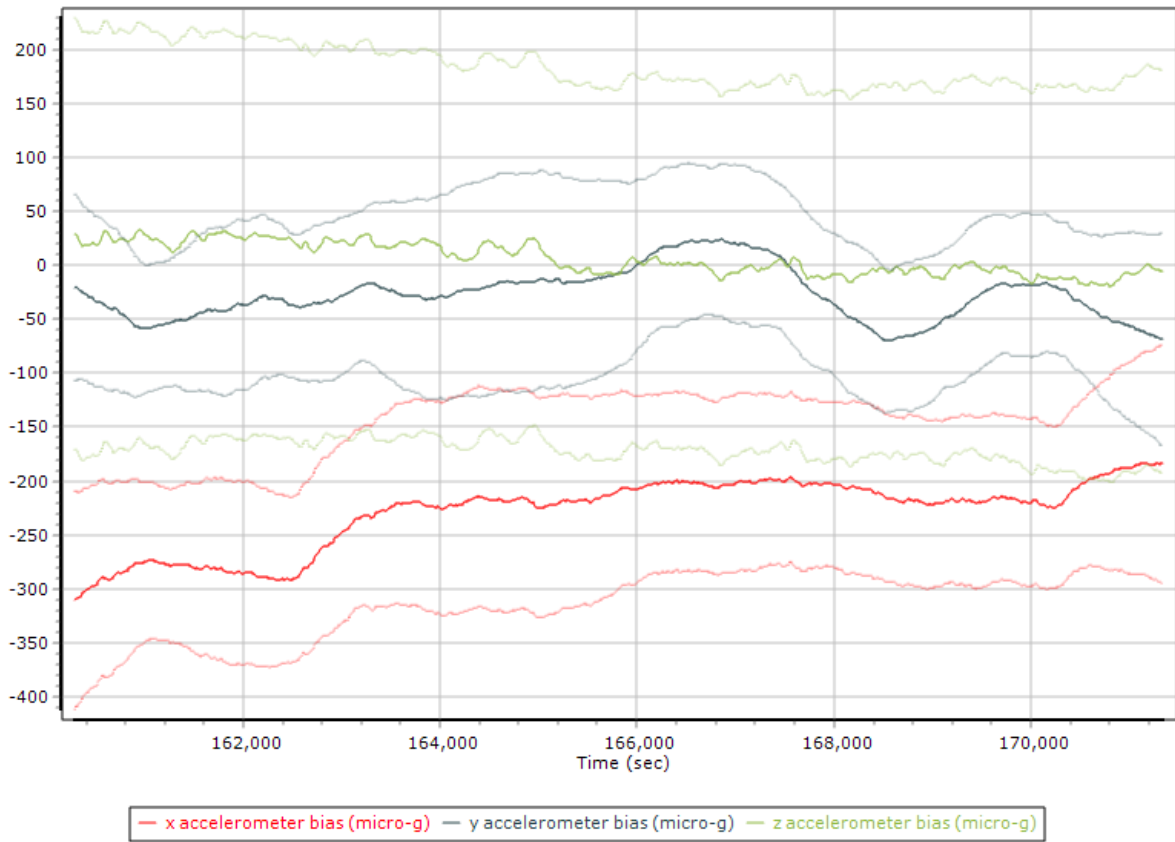
Processable Time Windows

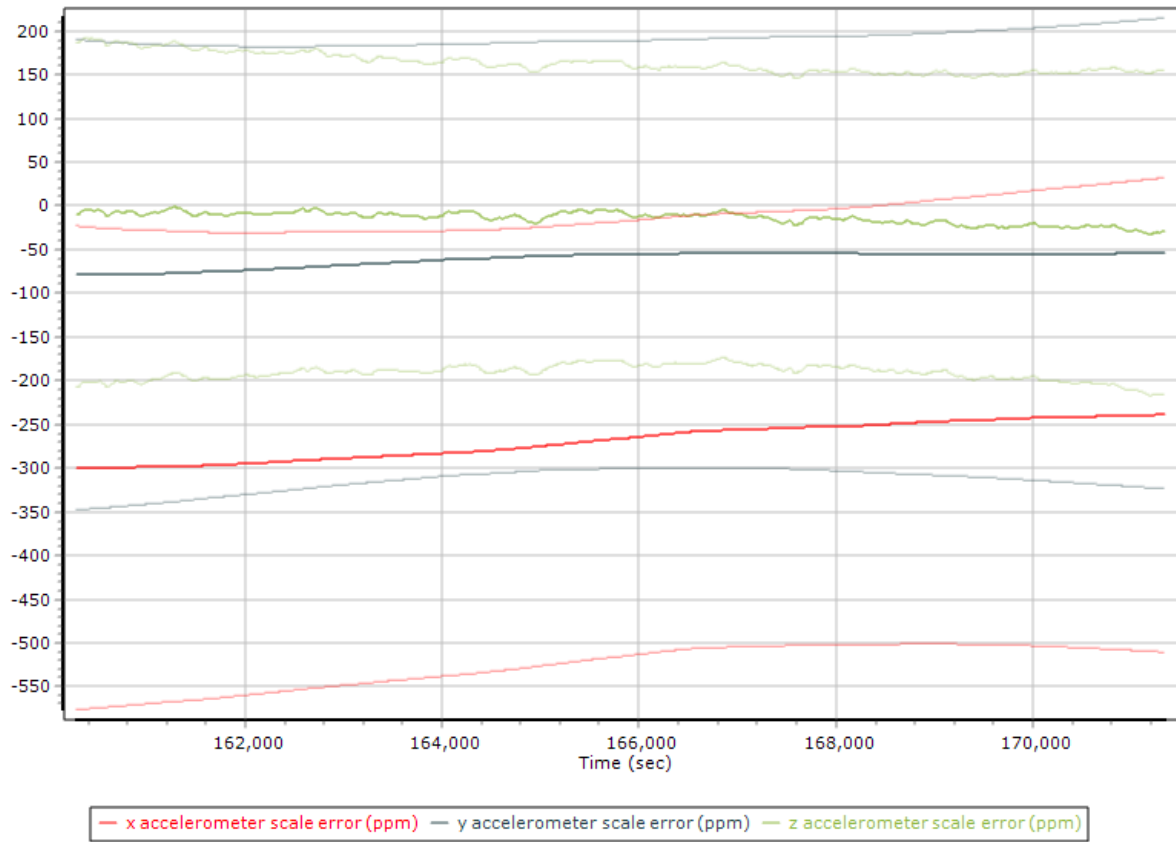
Start after launch Wait Time: 4.000 sec

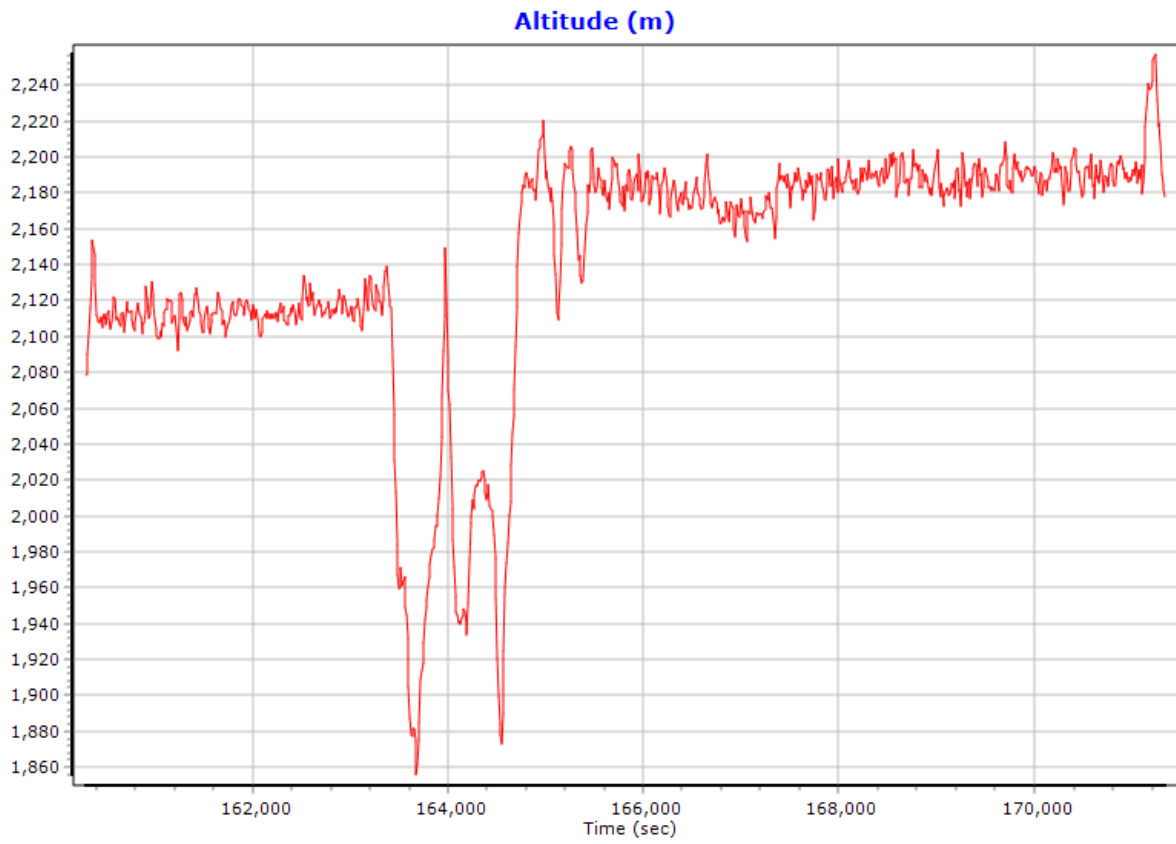
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	136926.000	155232.000	18306.000	End of file

OK Cancel

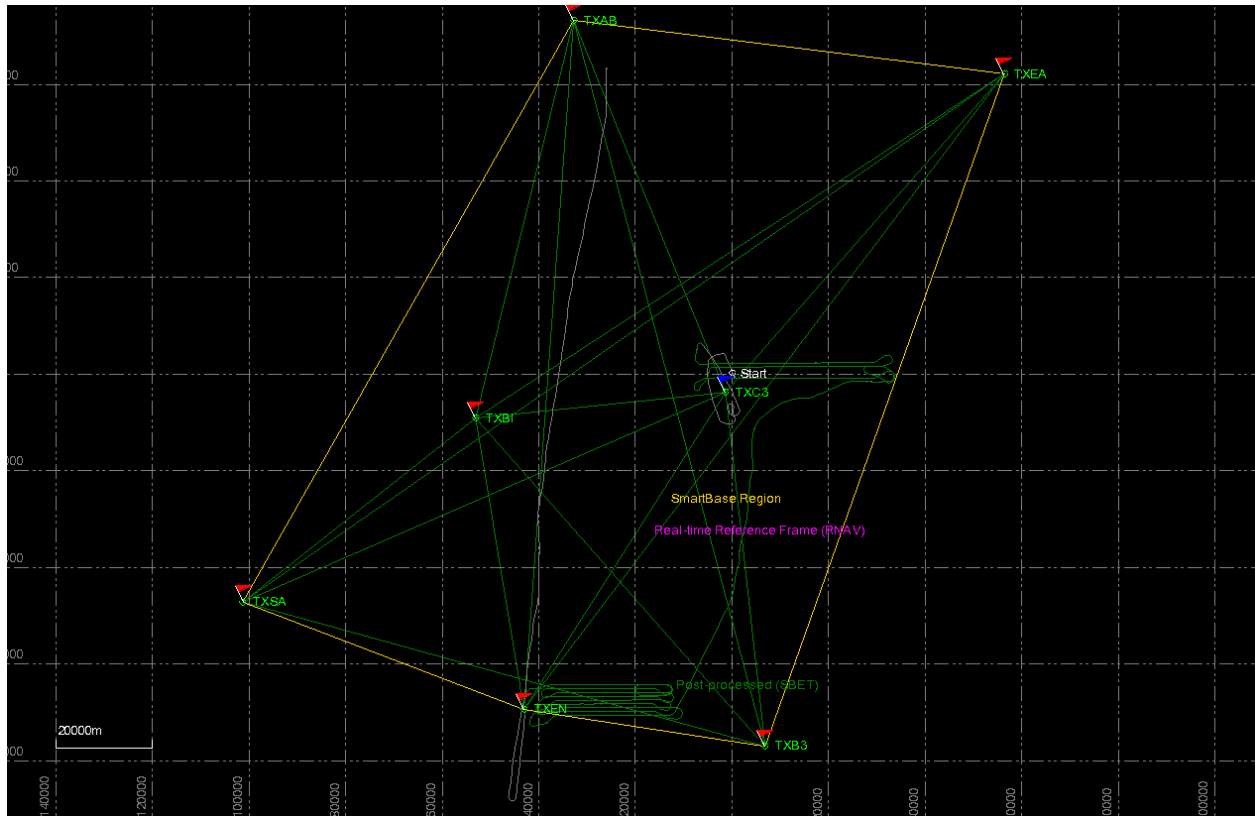
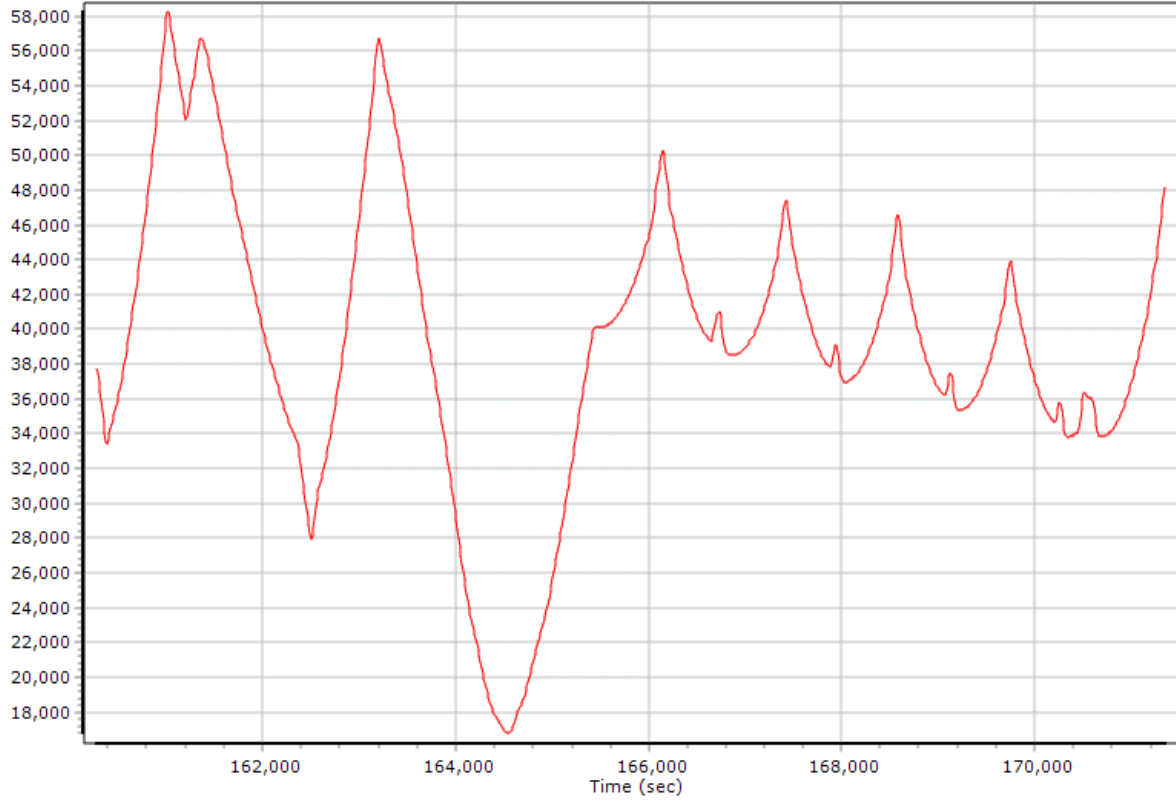
CAU18064B

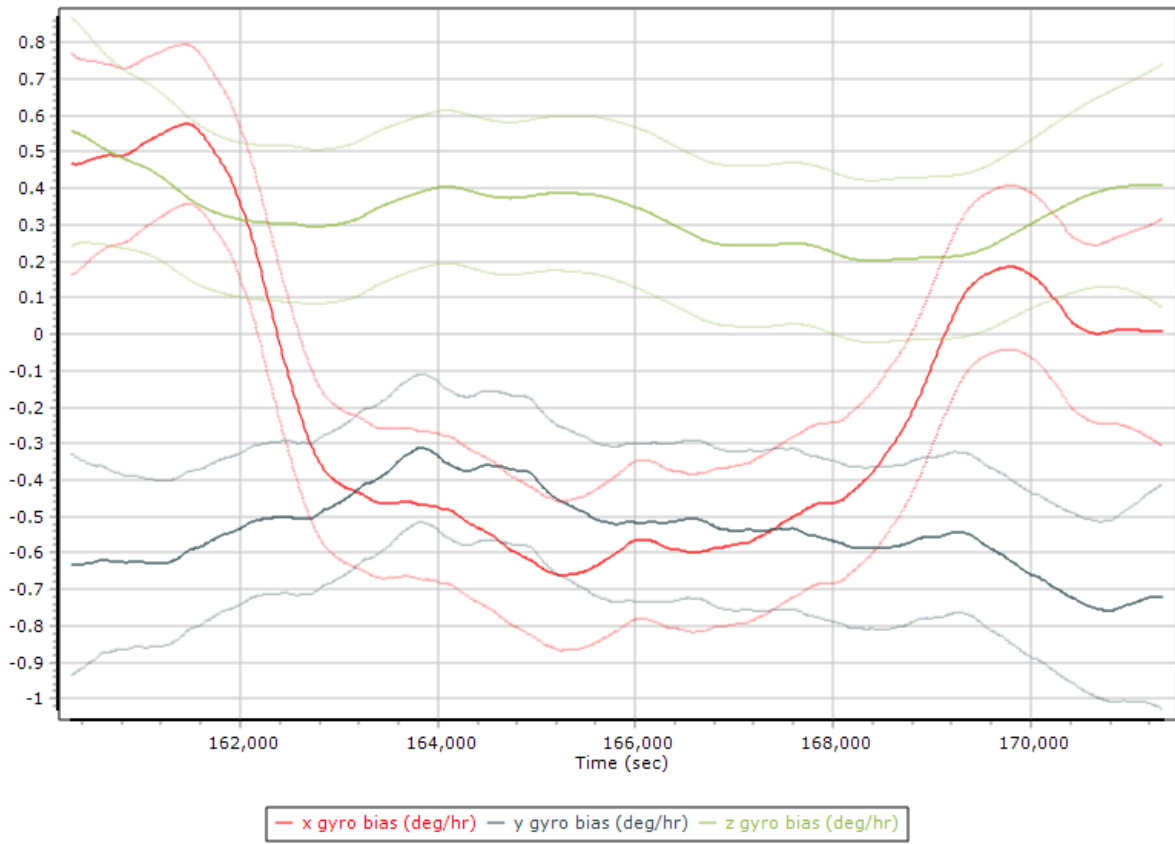


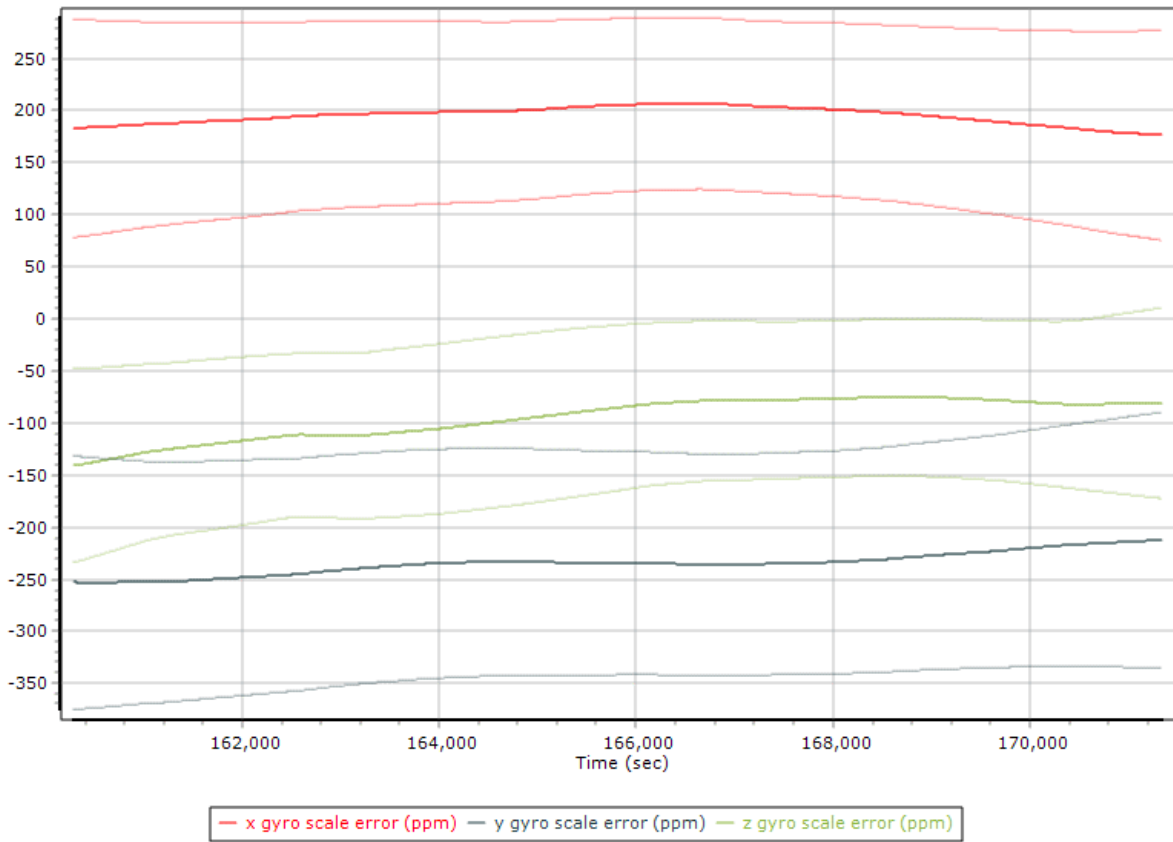




Baseline Length (m)







Project Settings ✕

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

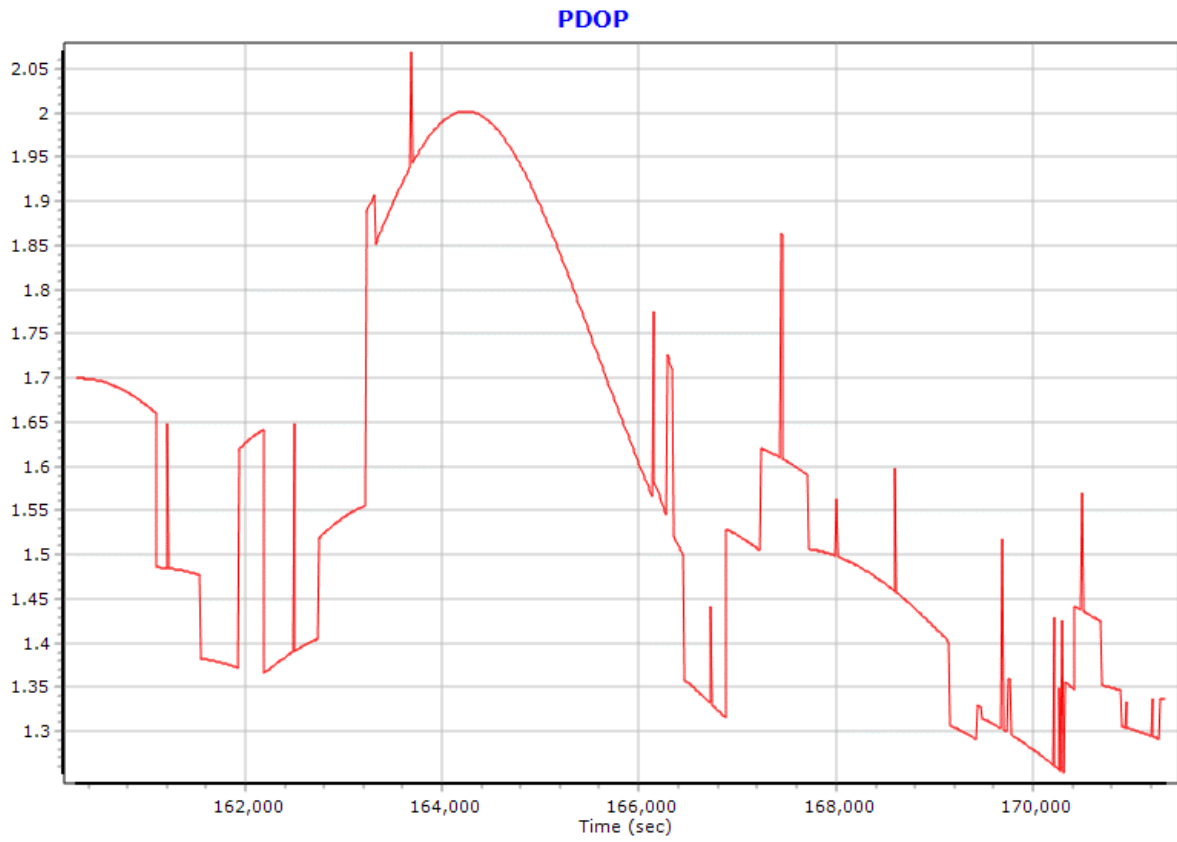
<3cm 10cm 50cm 1m 10m

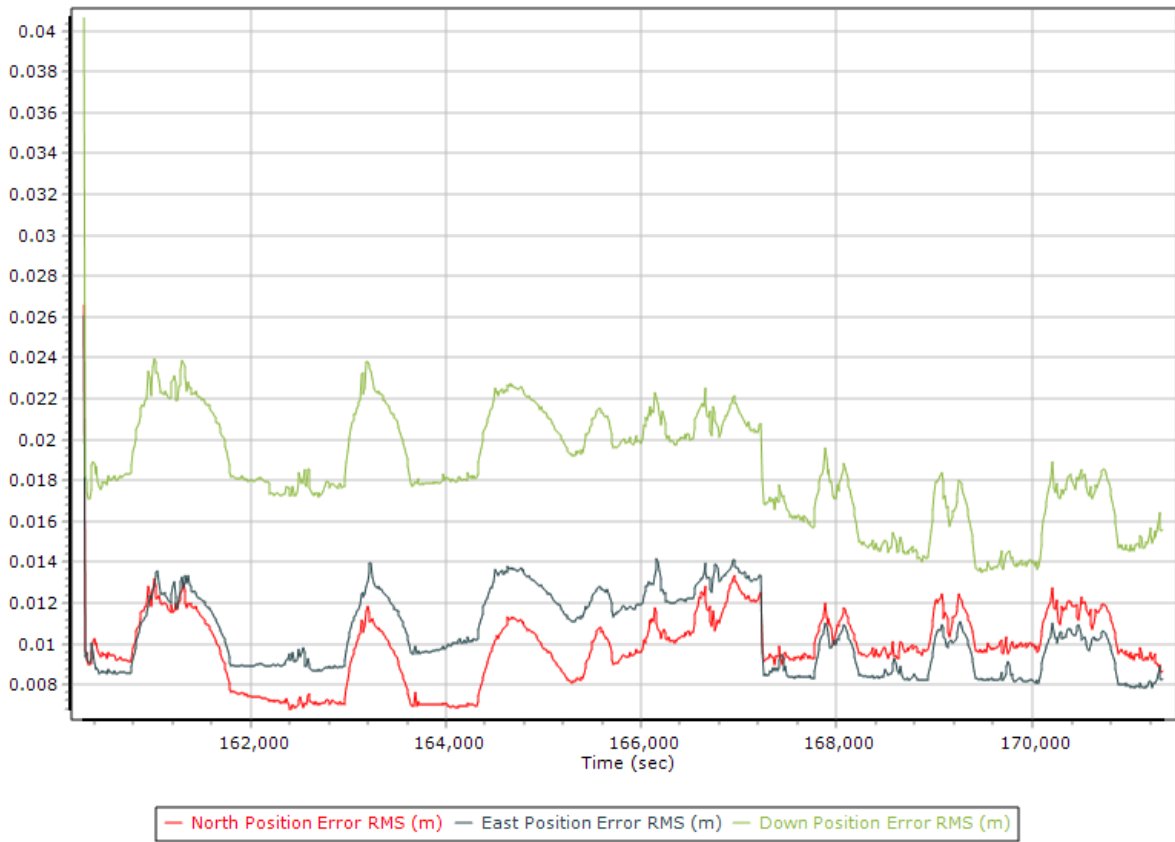
Aircraft to Reference Mounting Angles

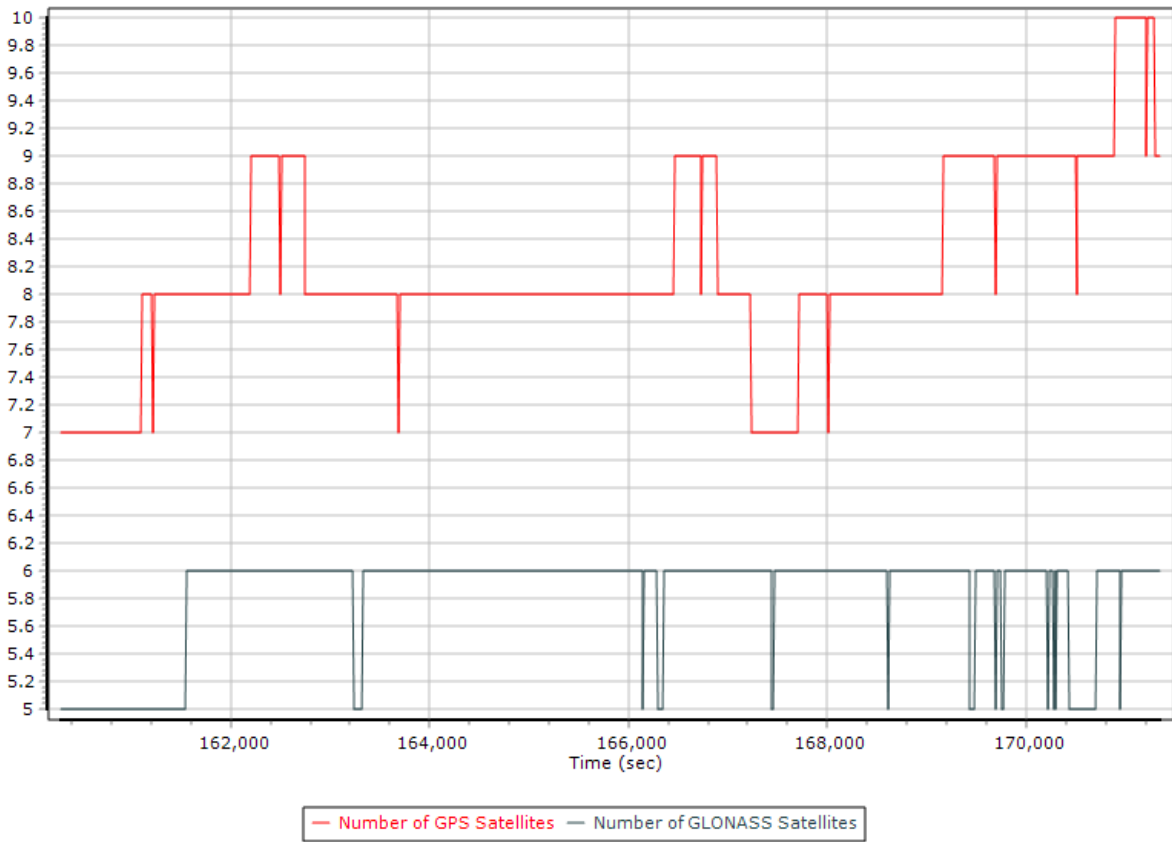
X:

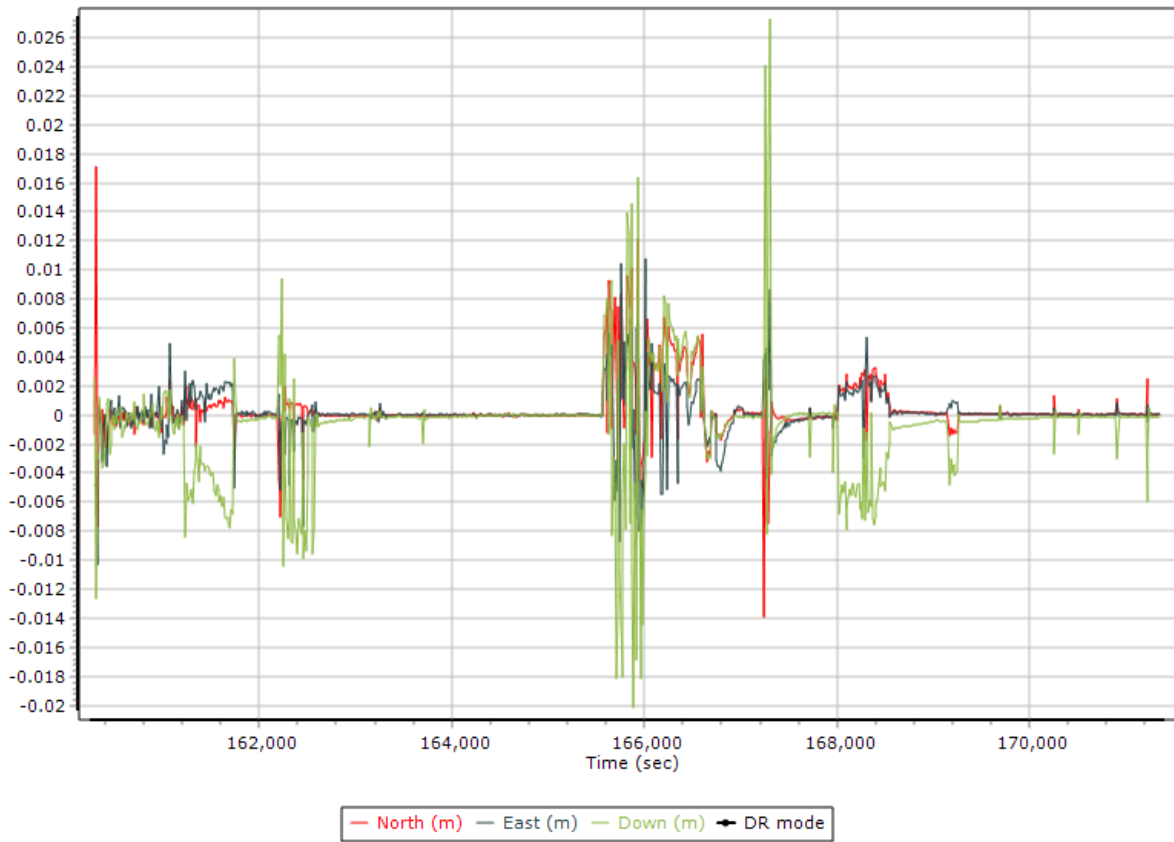
Y:

Z:









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: 158579.000
 End: 175191.000
 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

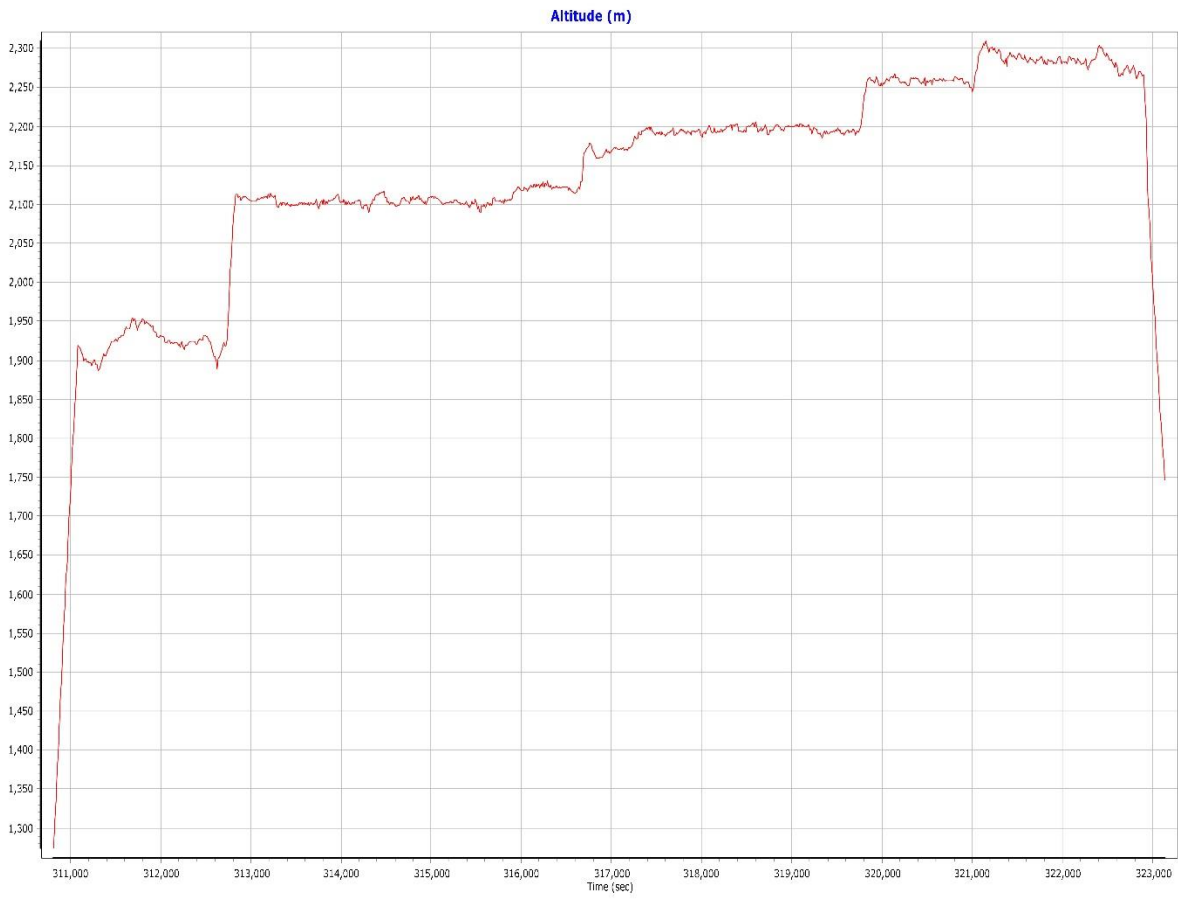
Processable Time Windows

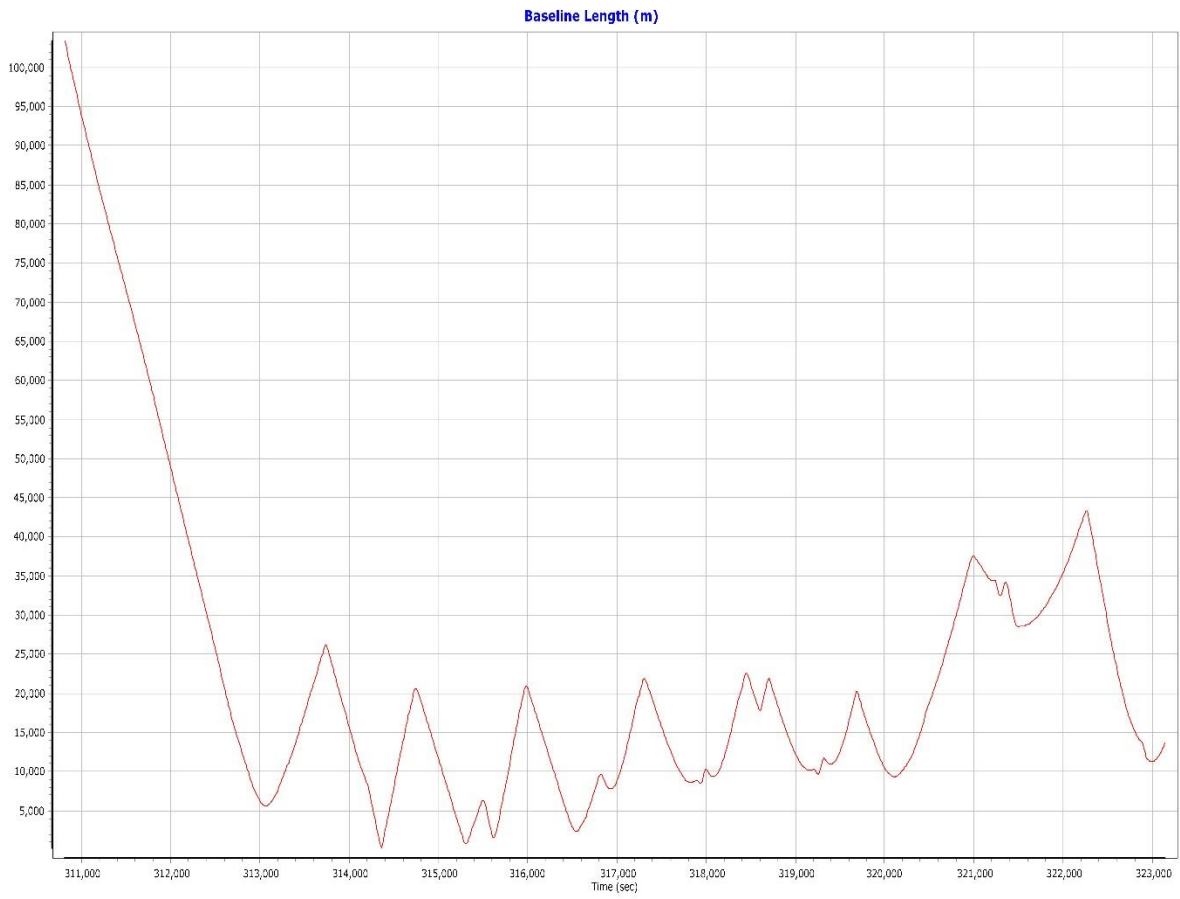
Start after launch Wait Time: 4.000 sec

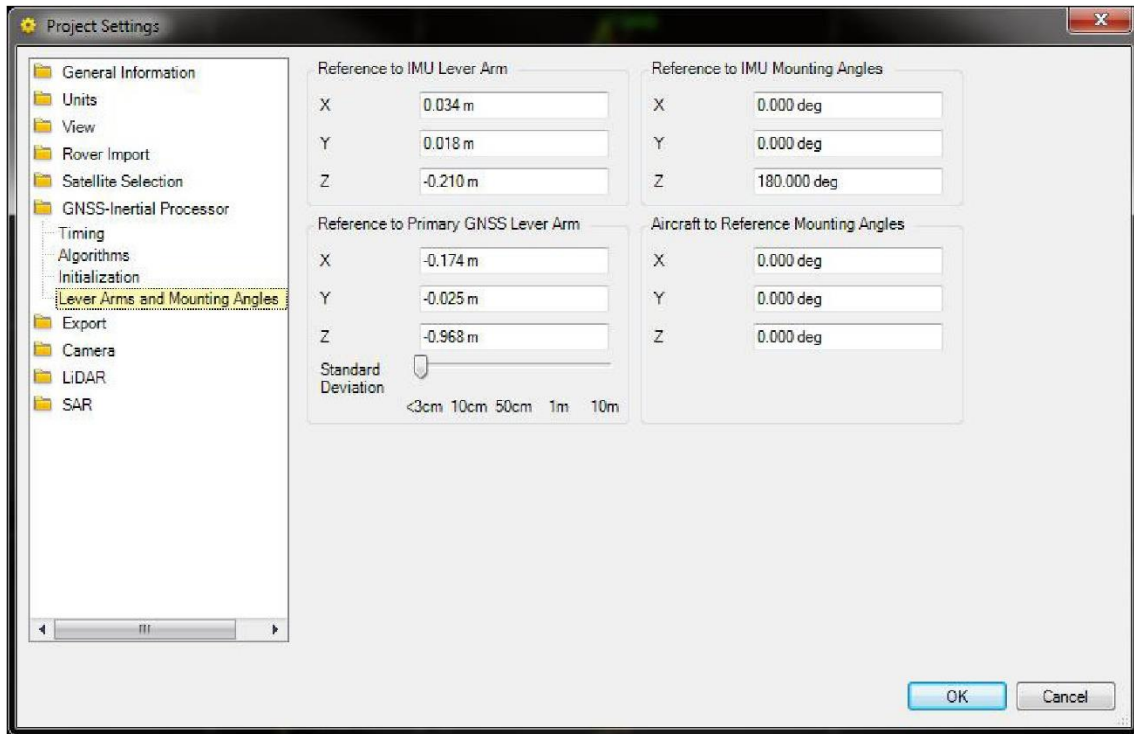
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	158579.000	175191.000	16612.000	End of file

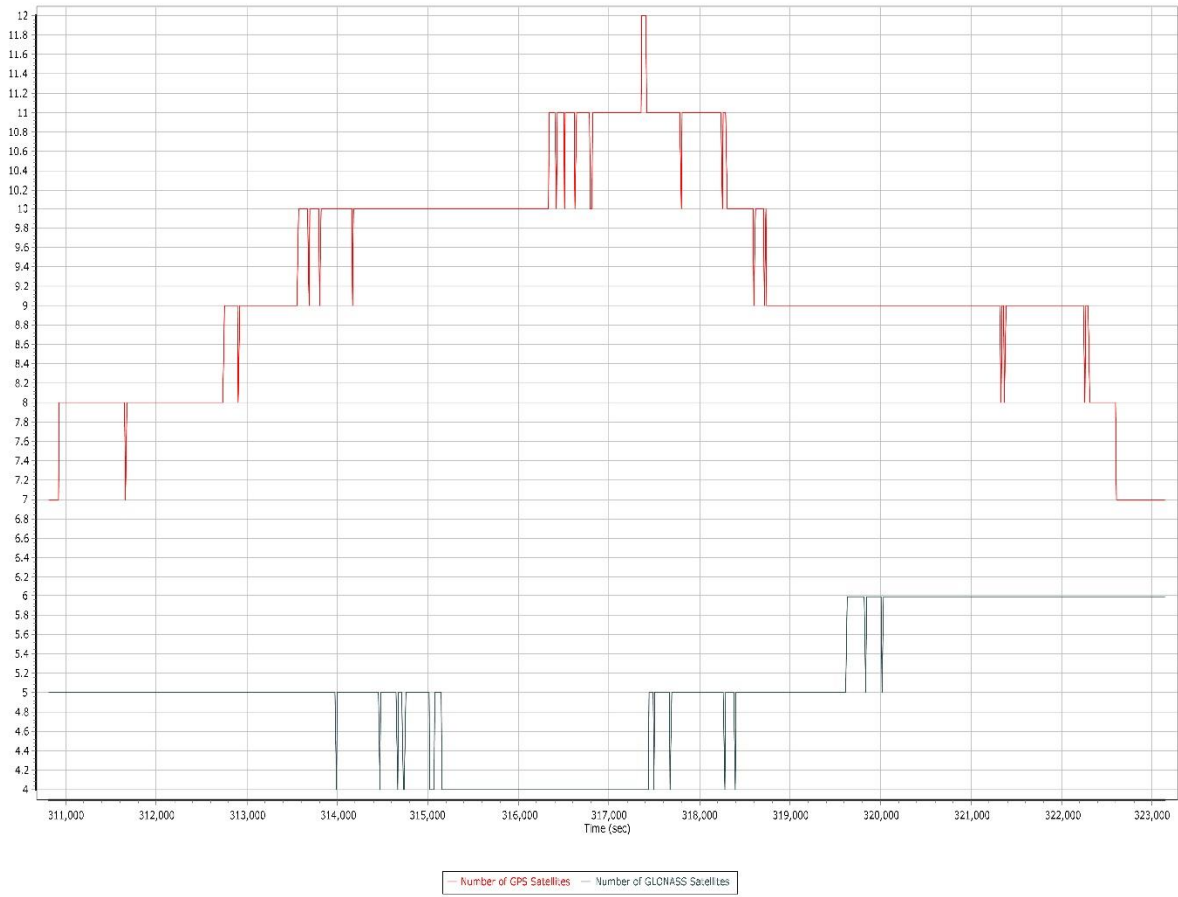
OK Cancel

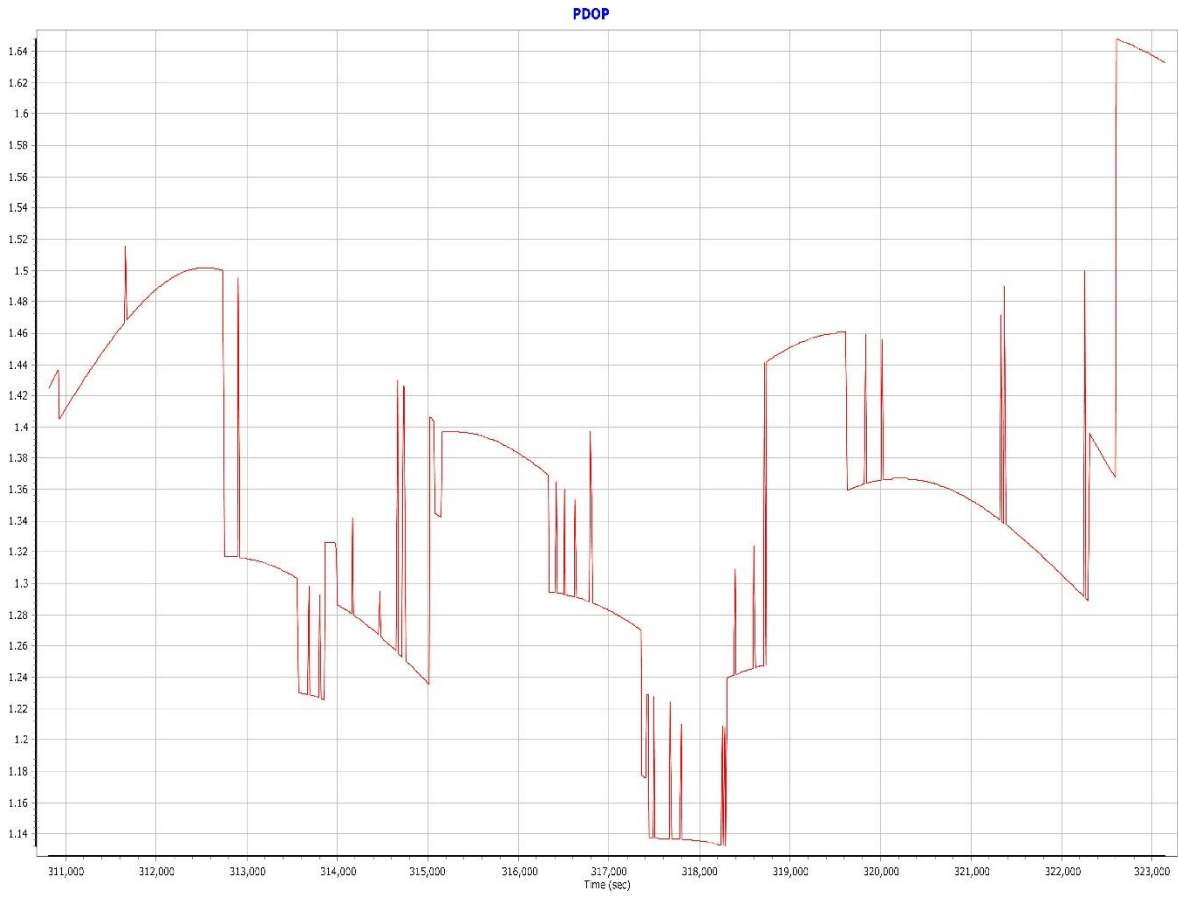
CAU18066A

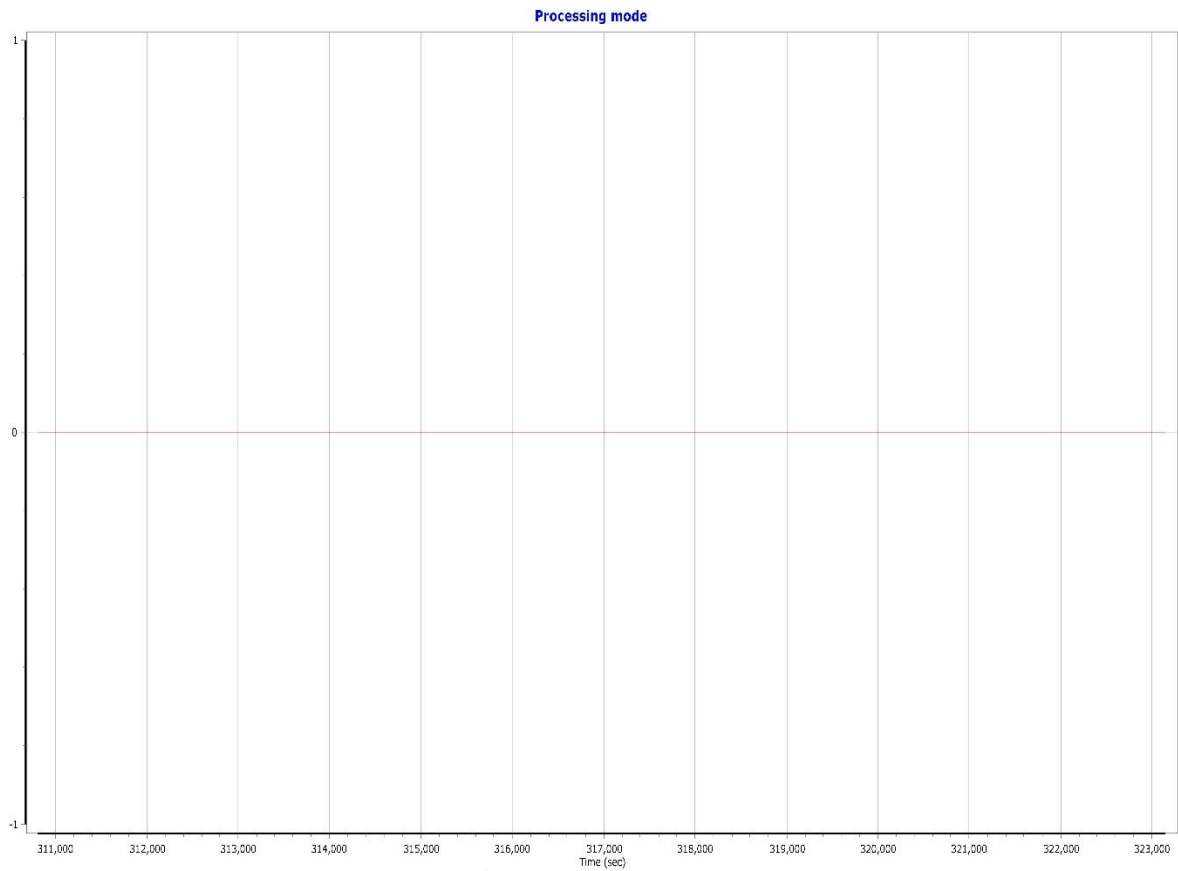






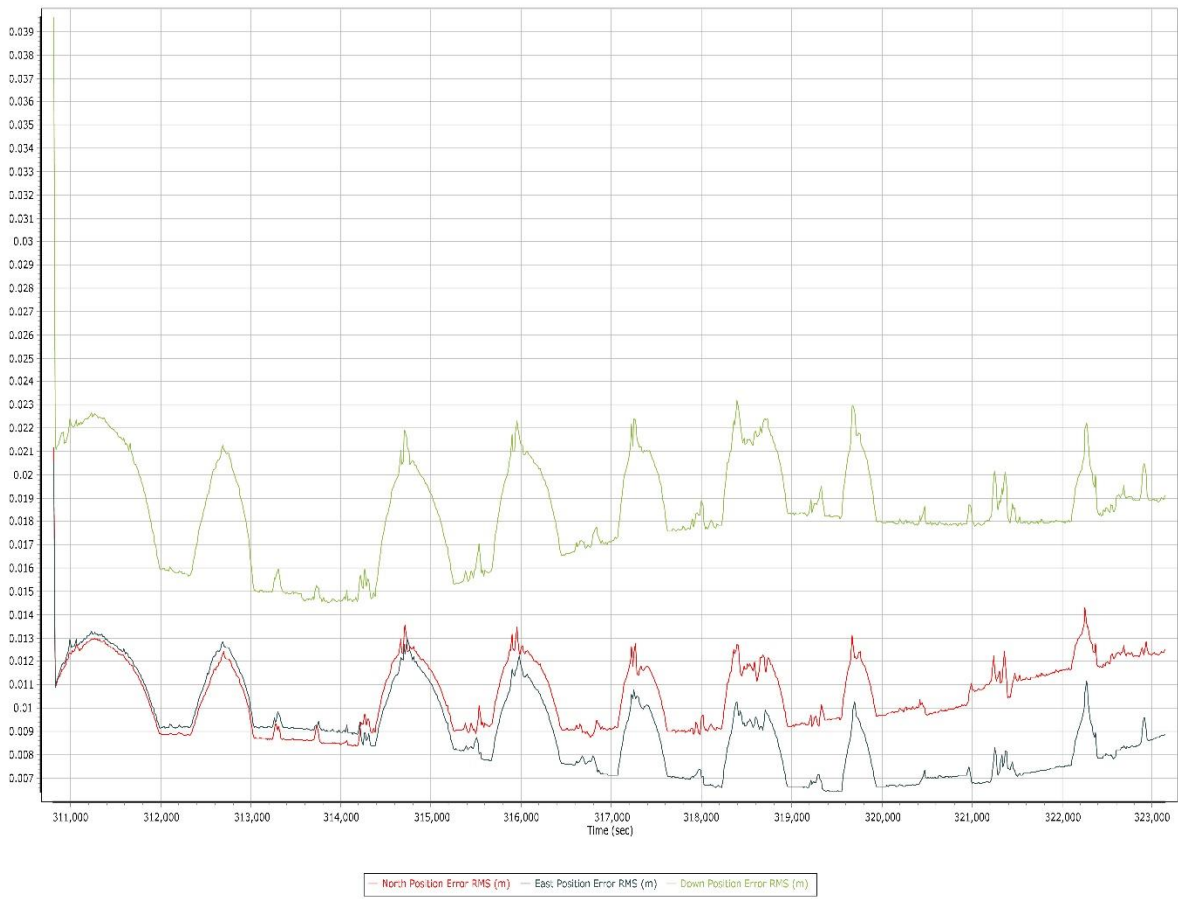


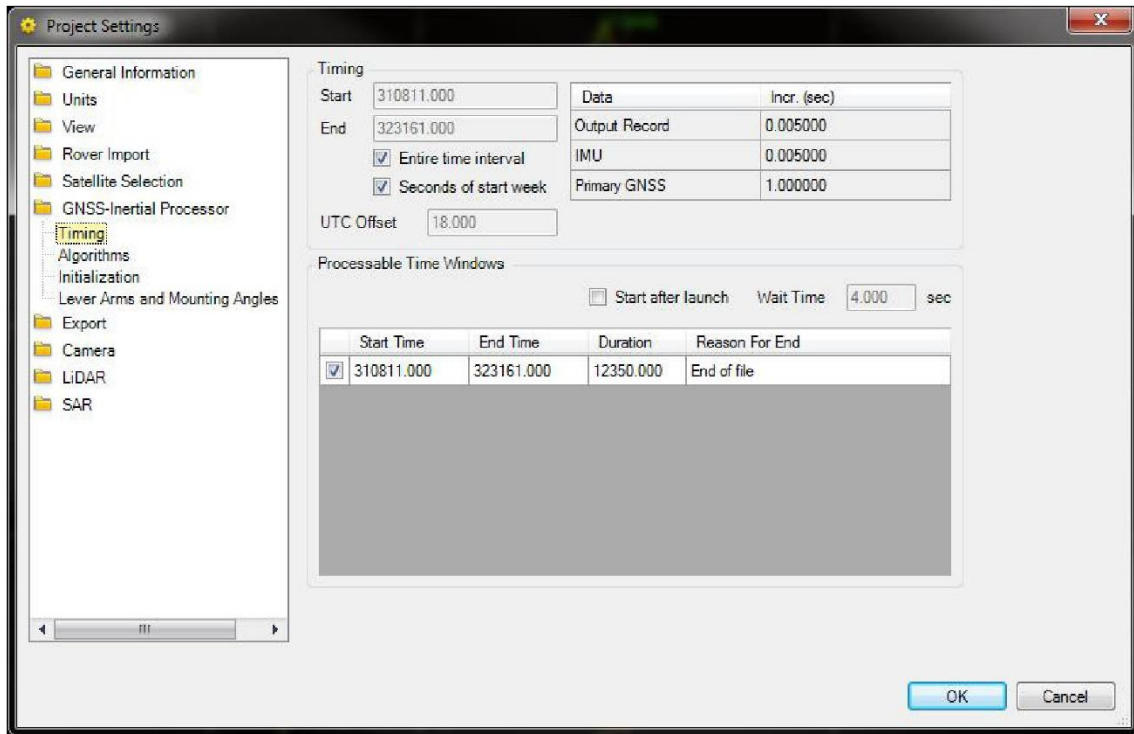


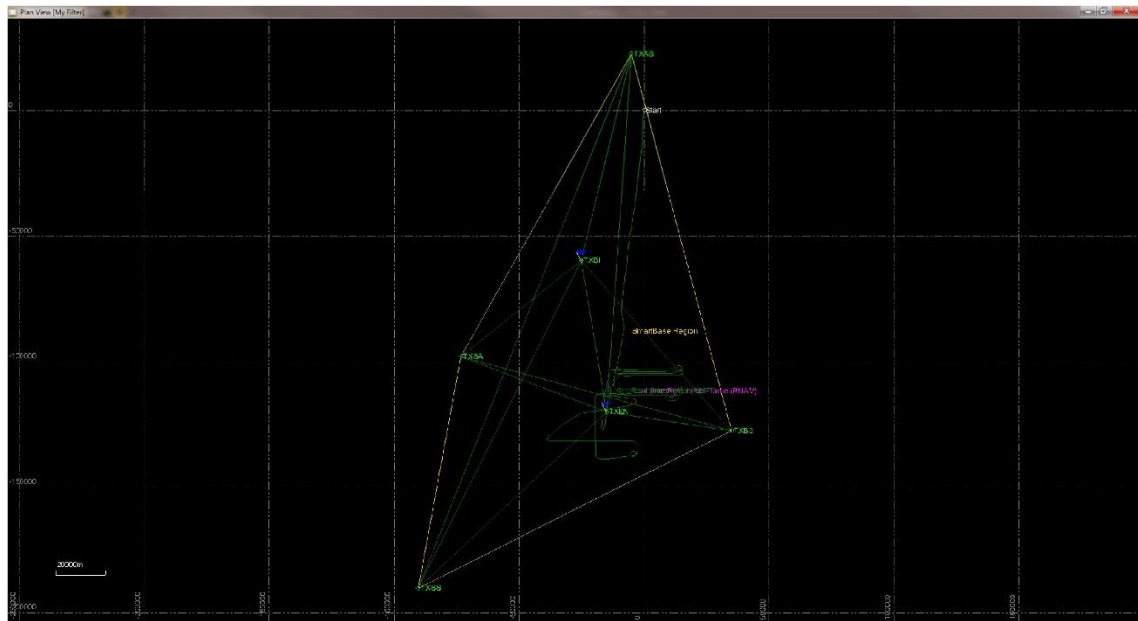


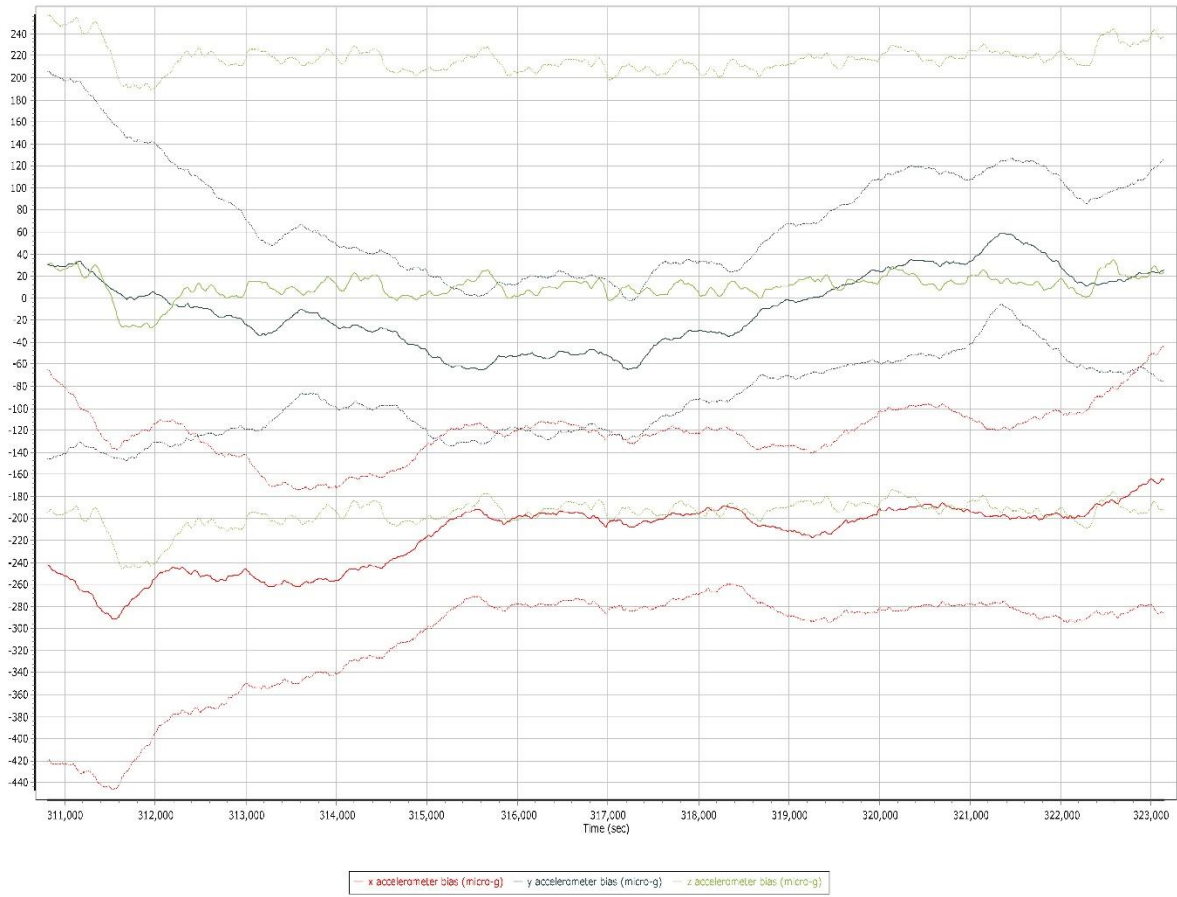
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IA PPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

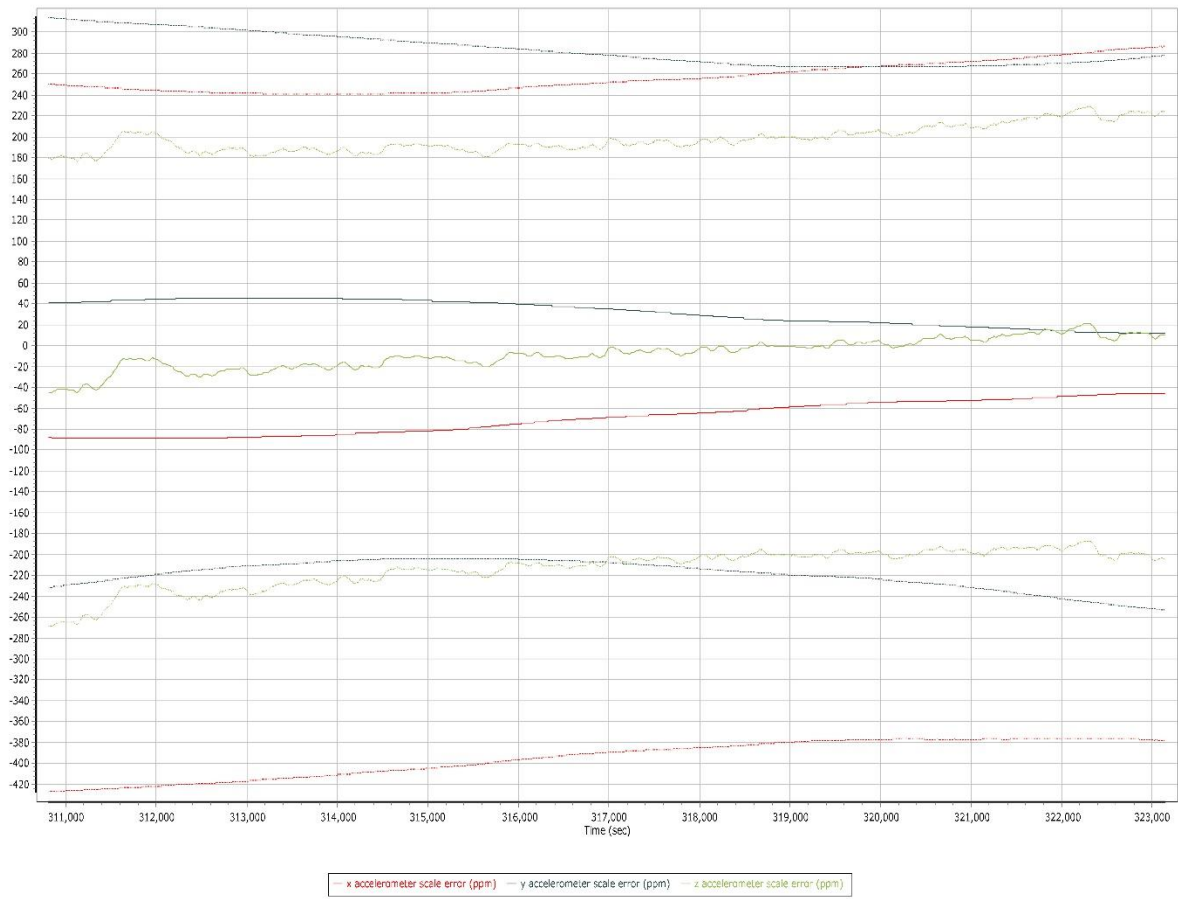


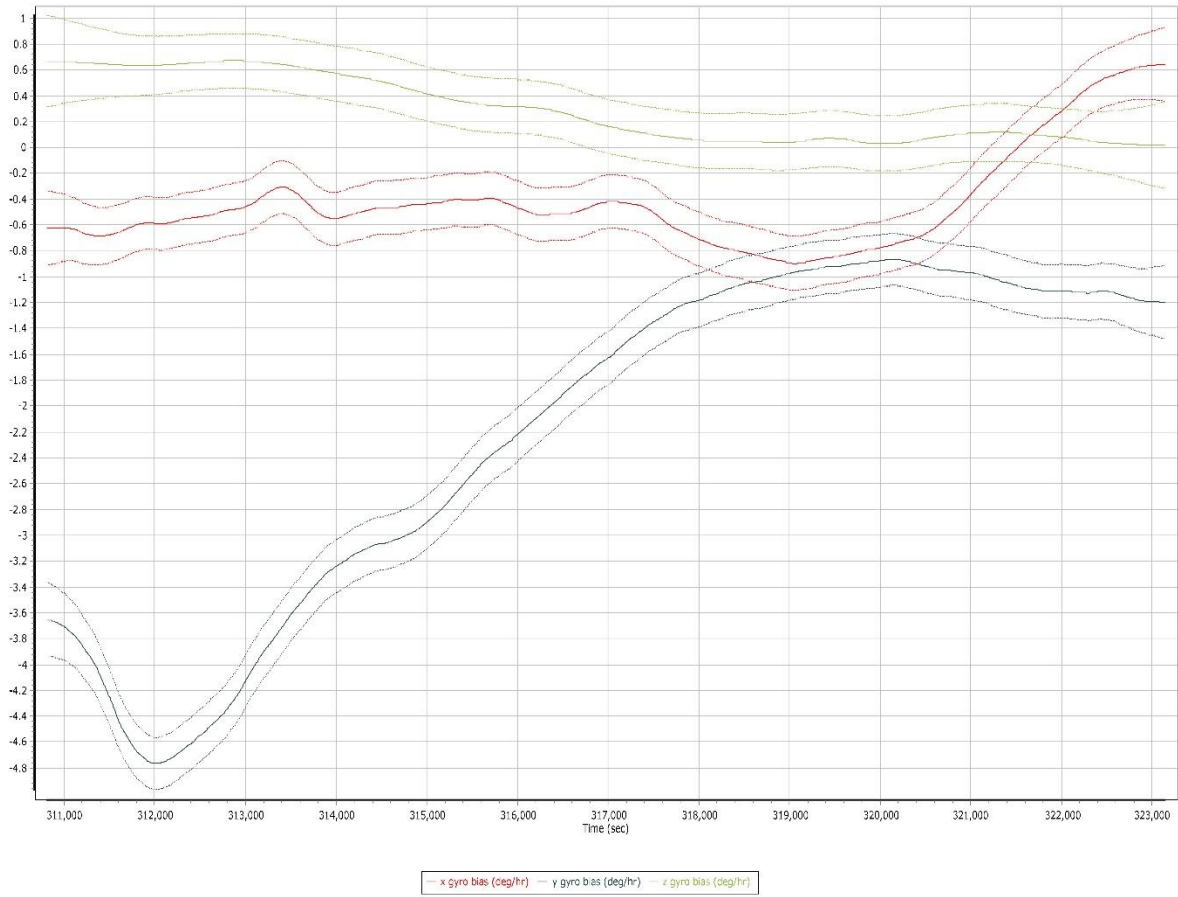


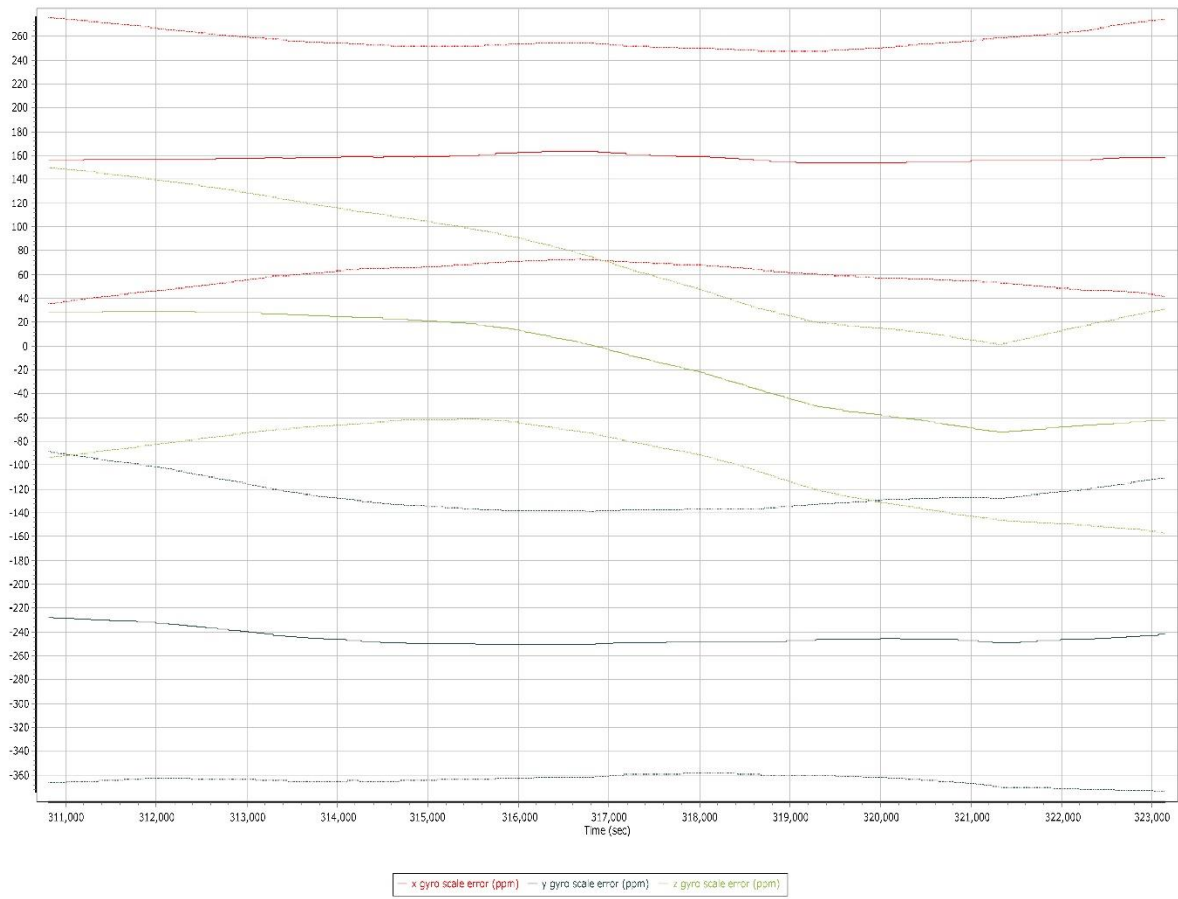




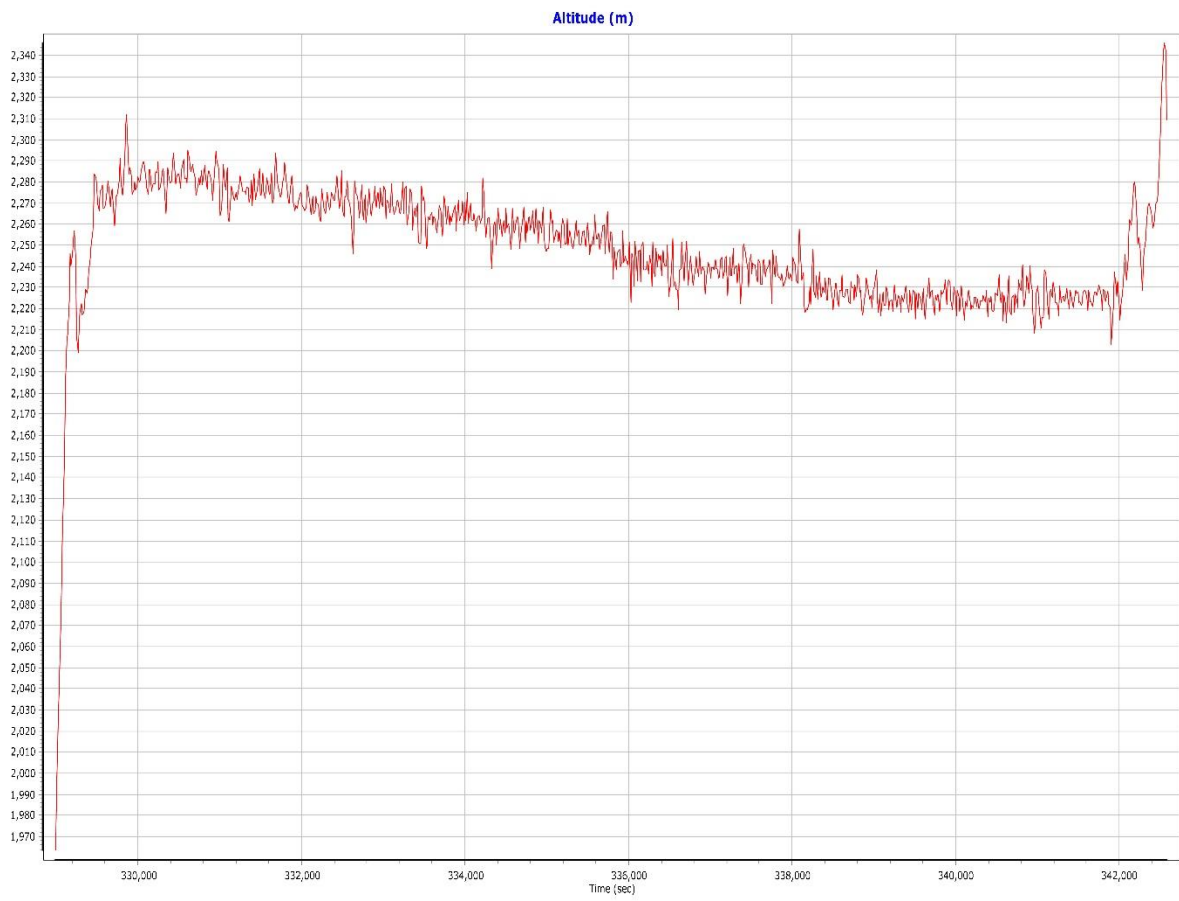


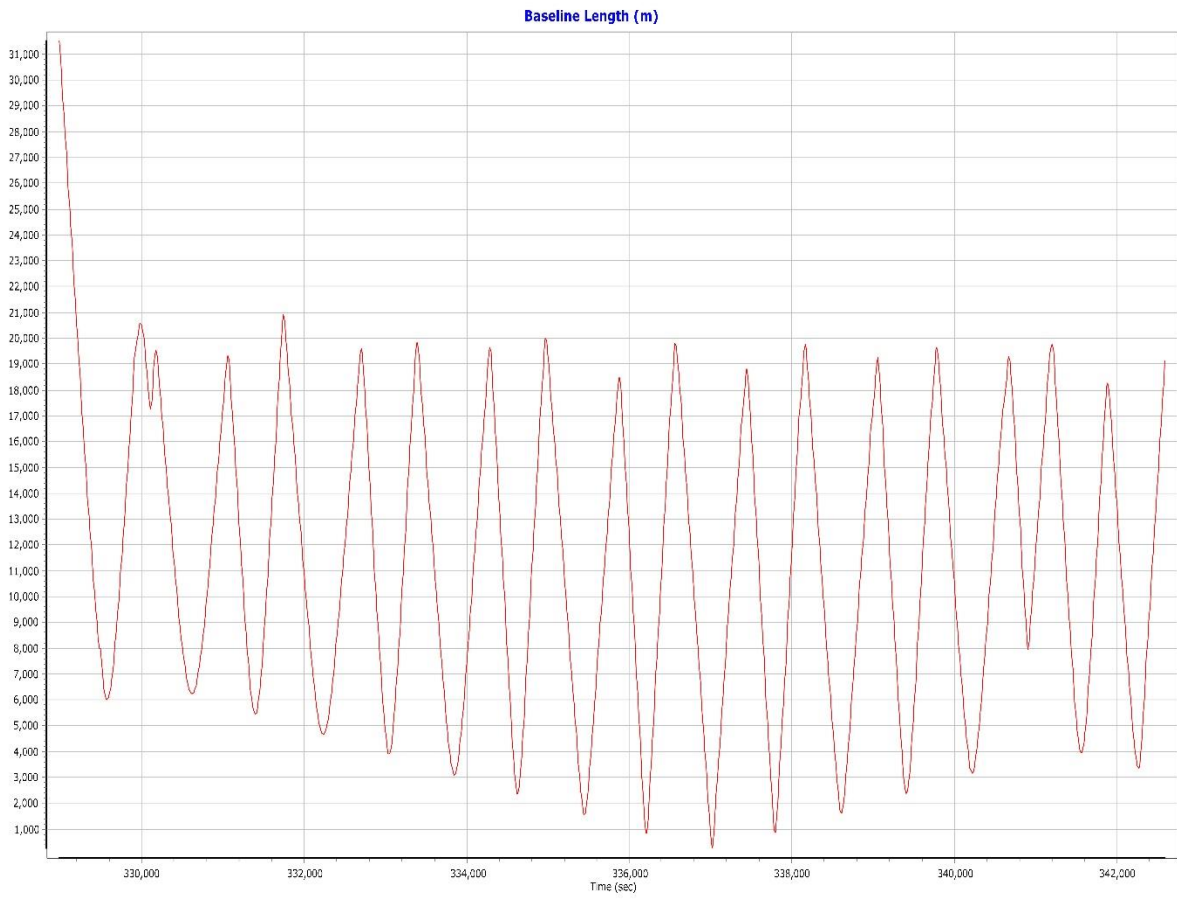


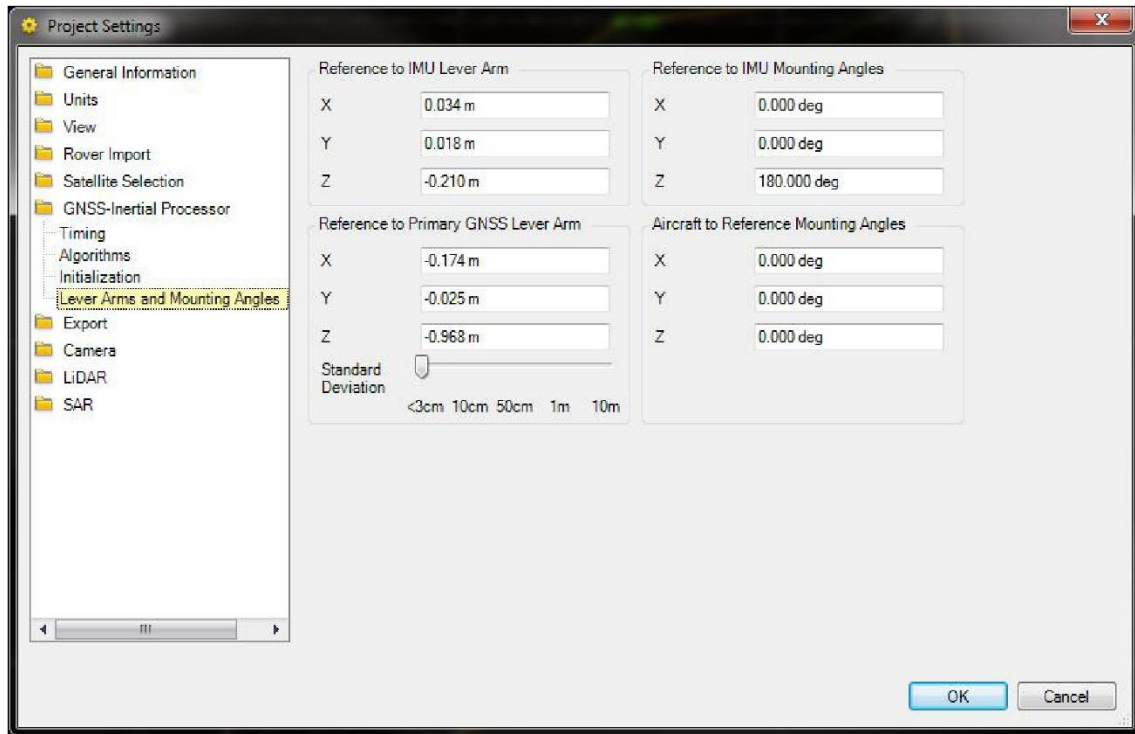


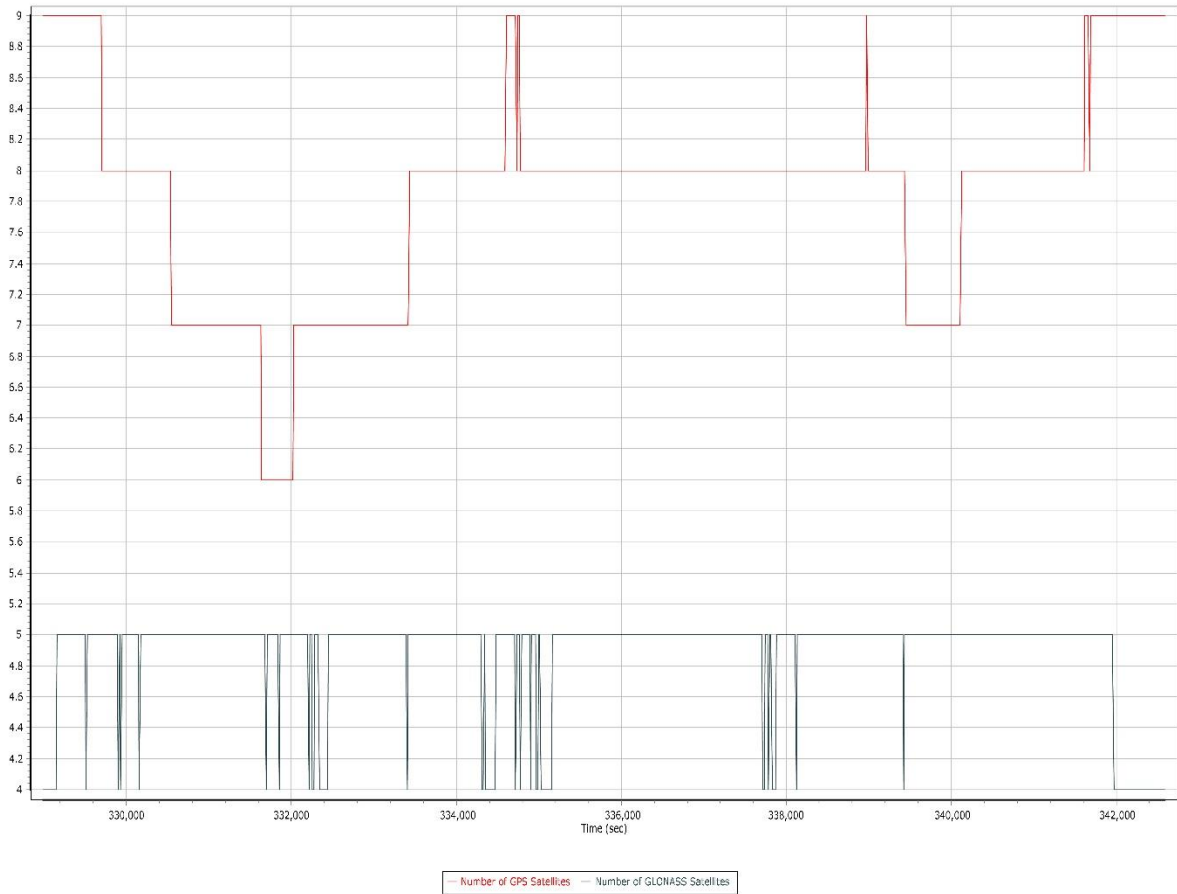


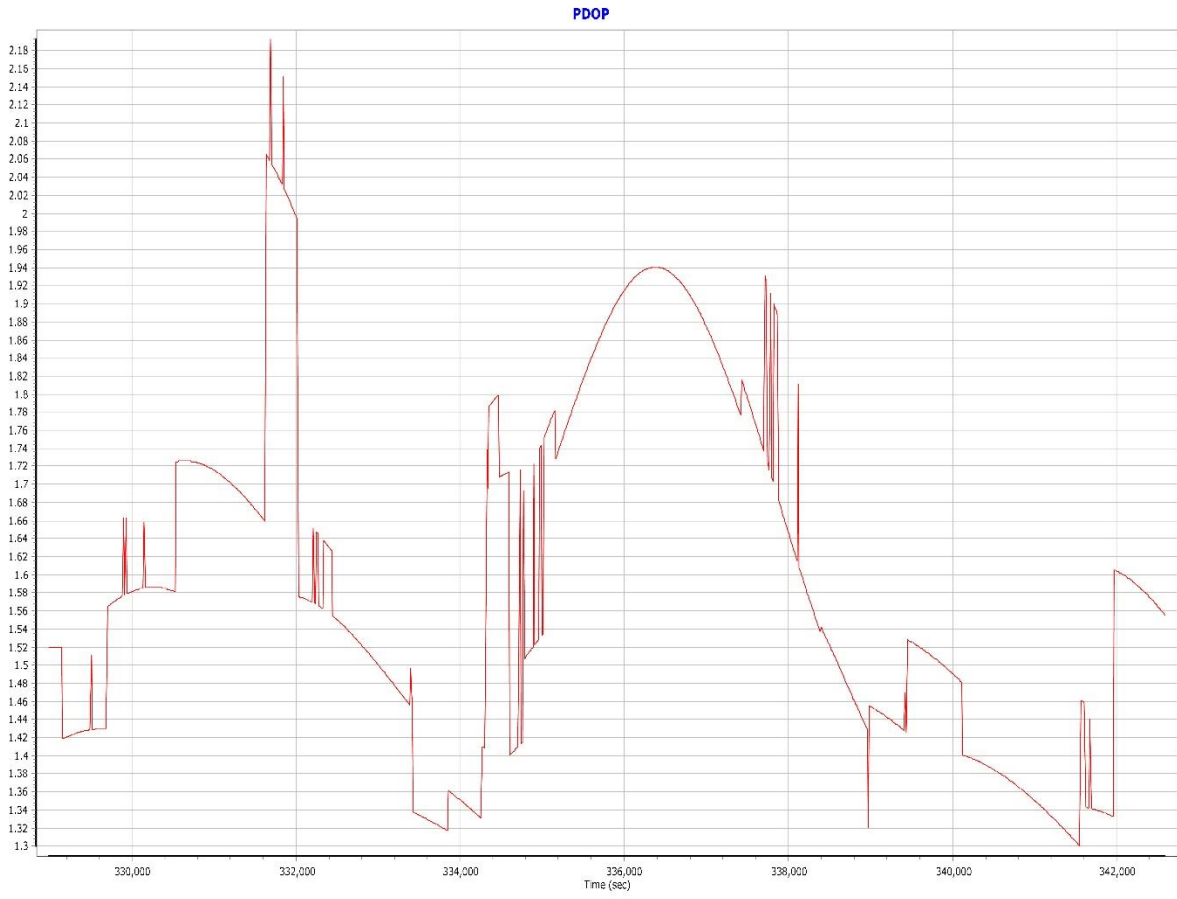
CAU18066B

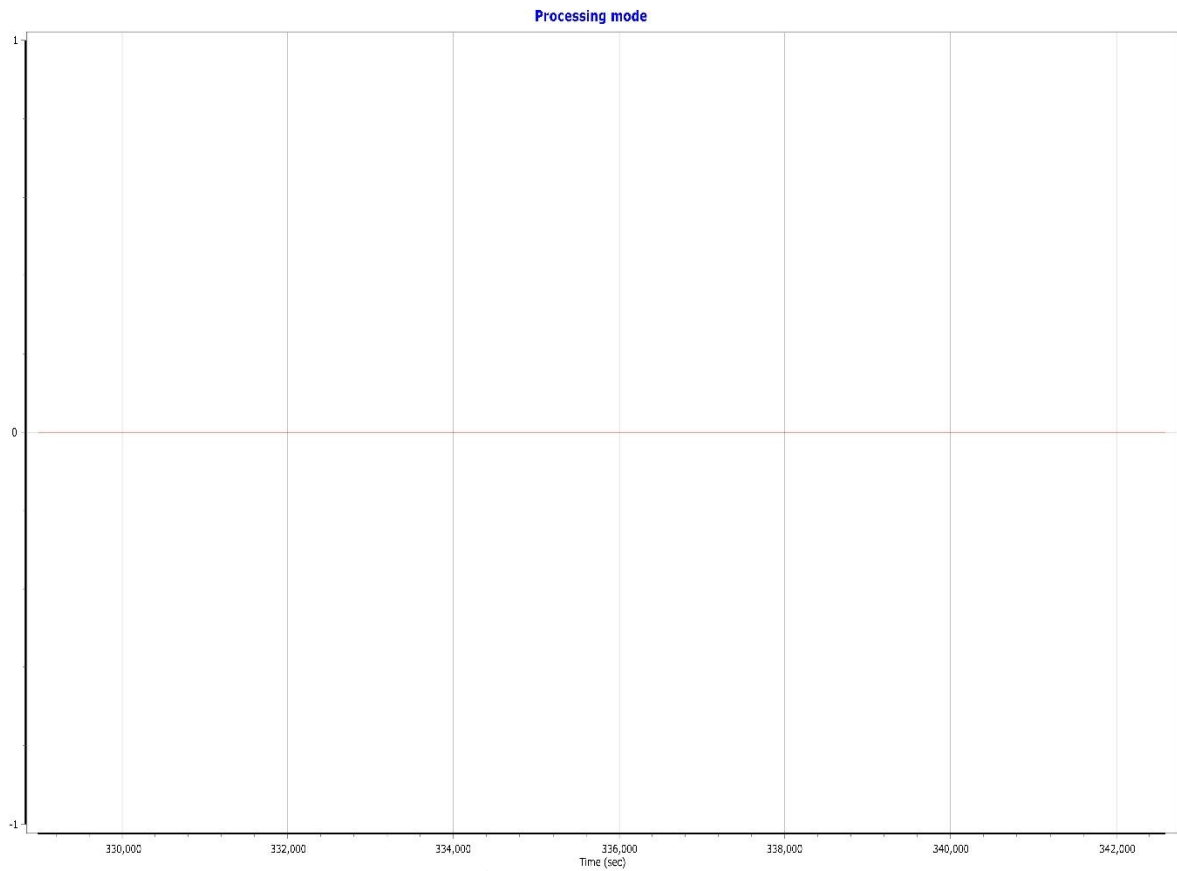




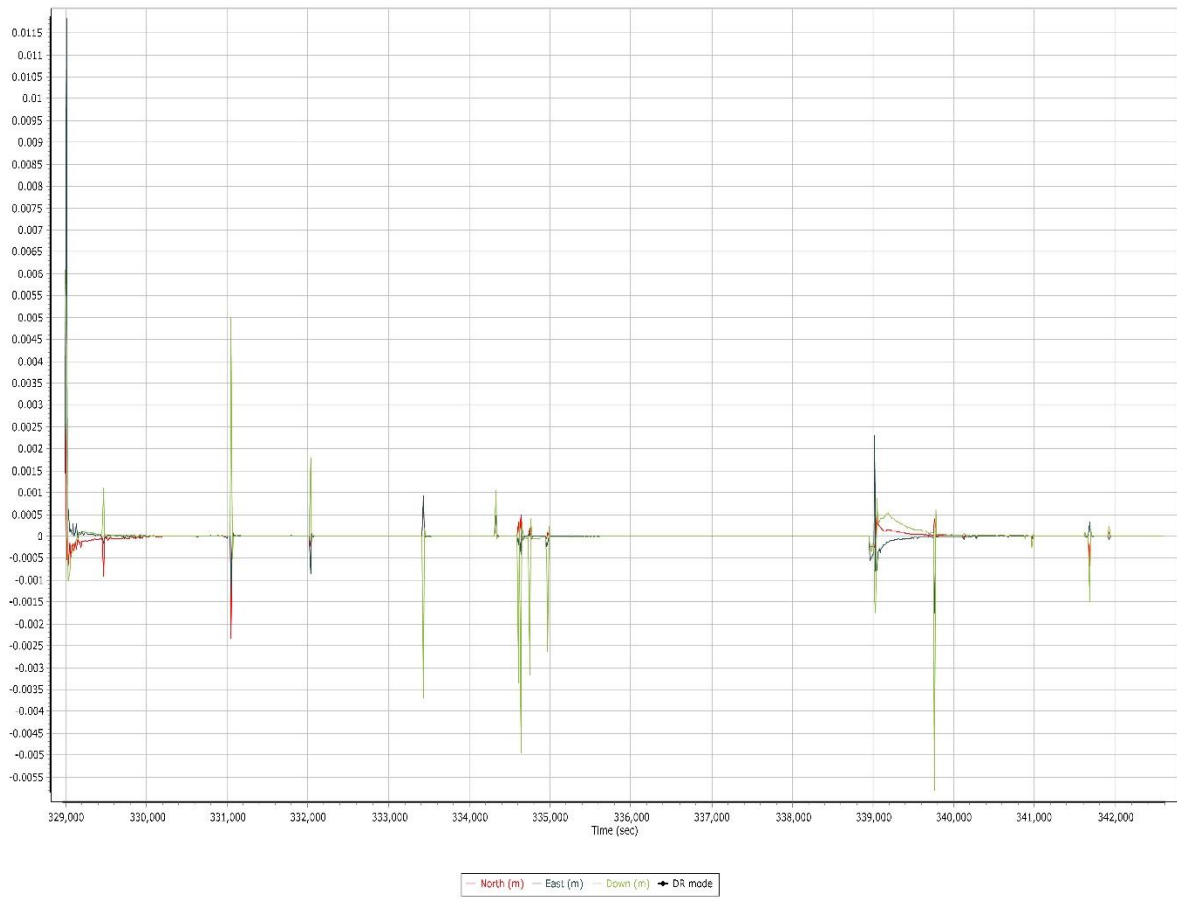


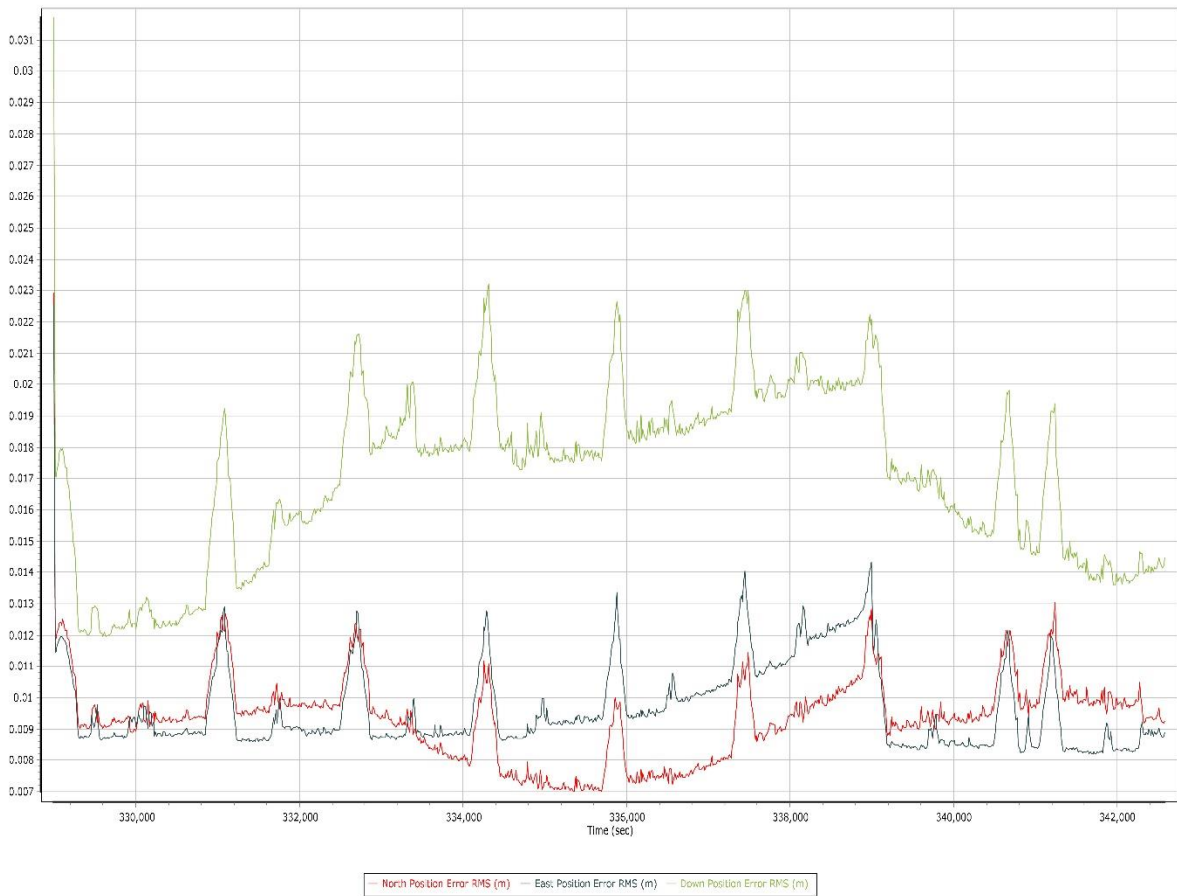


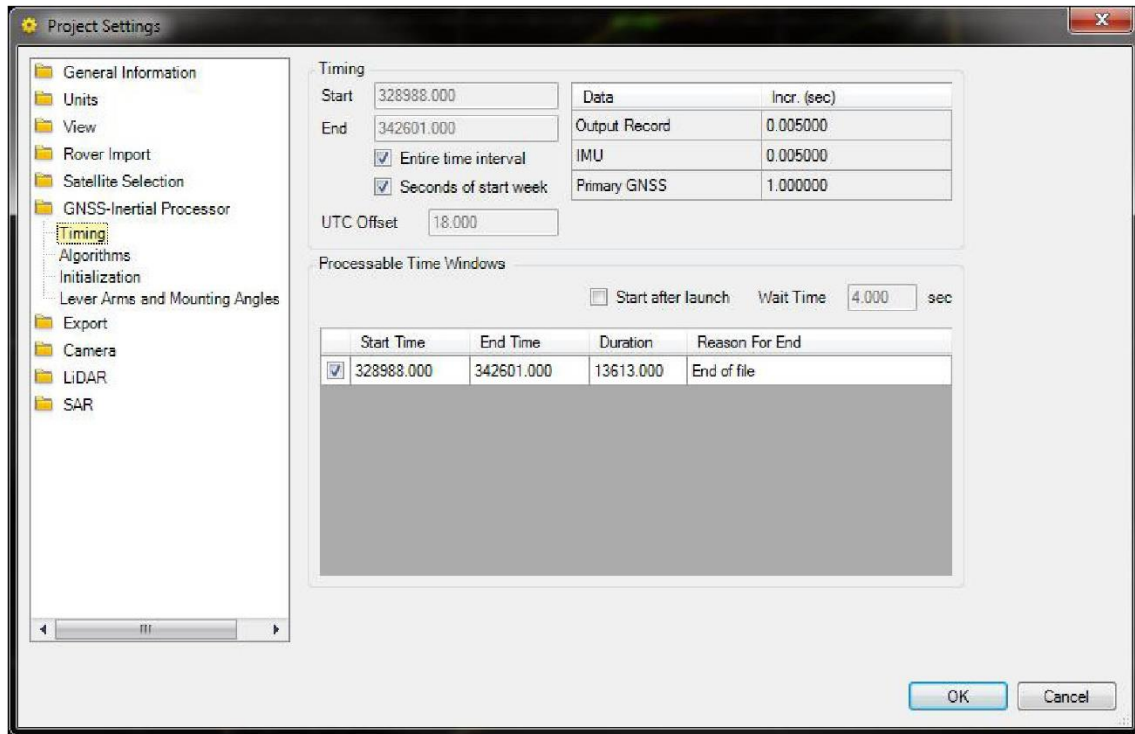


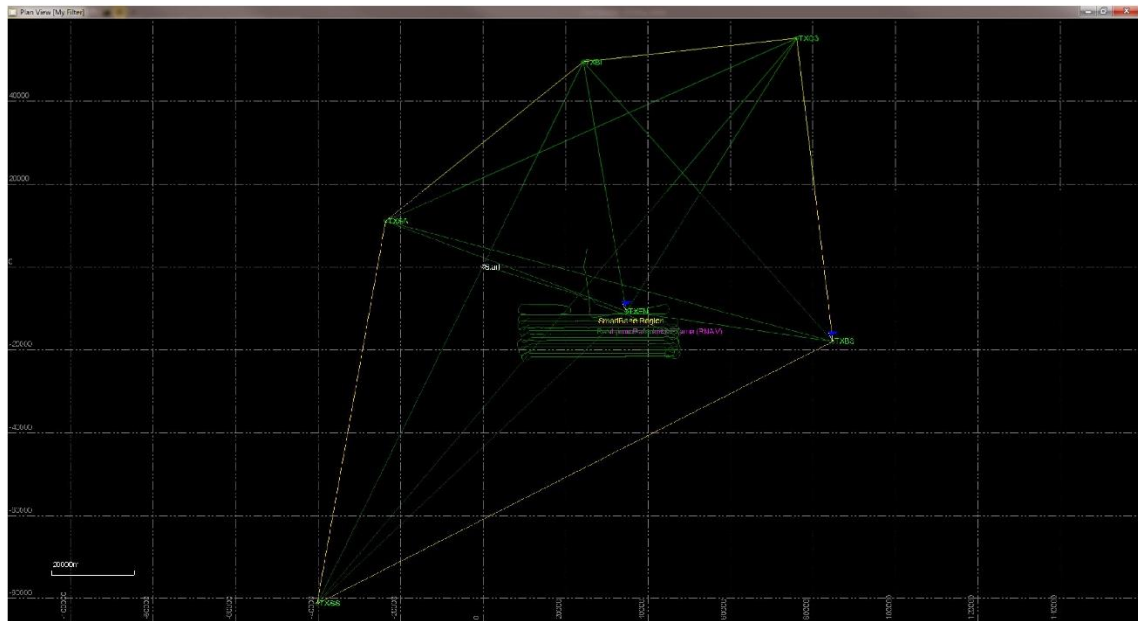


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IA PPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

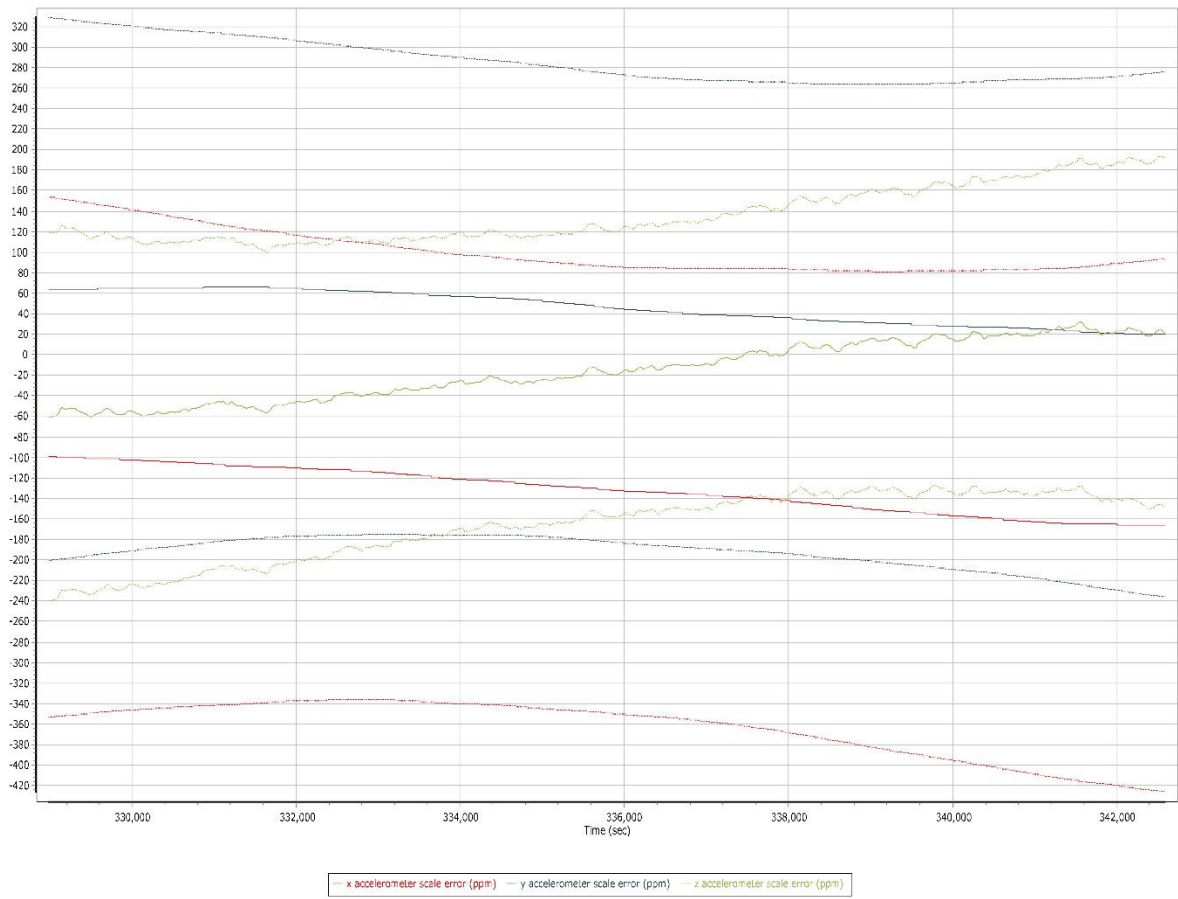


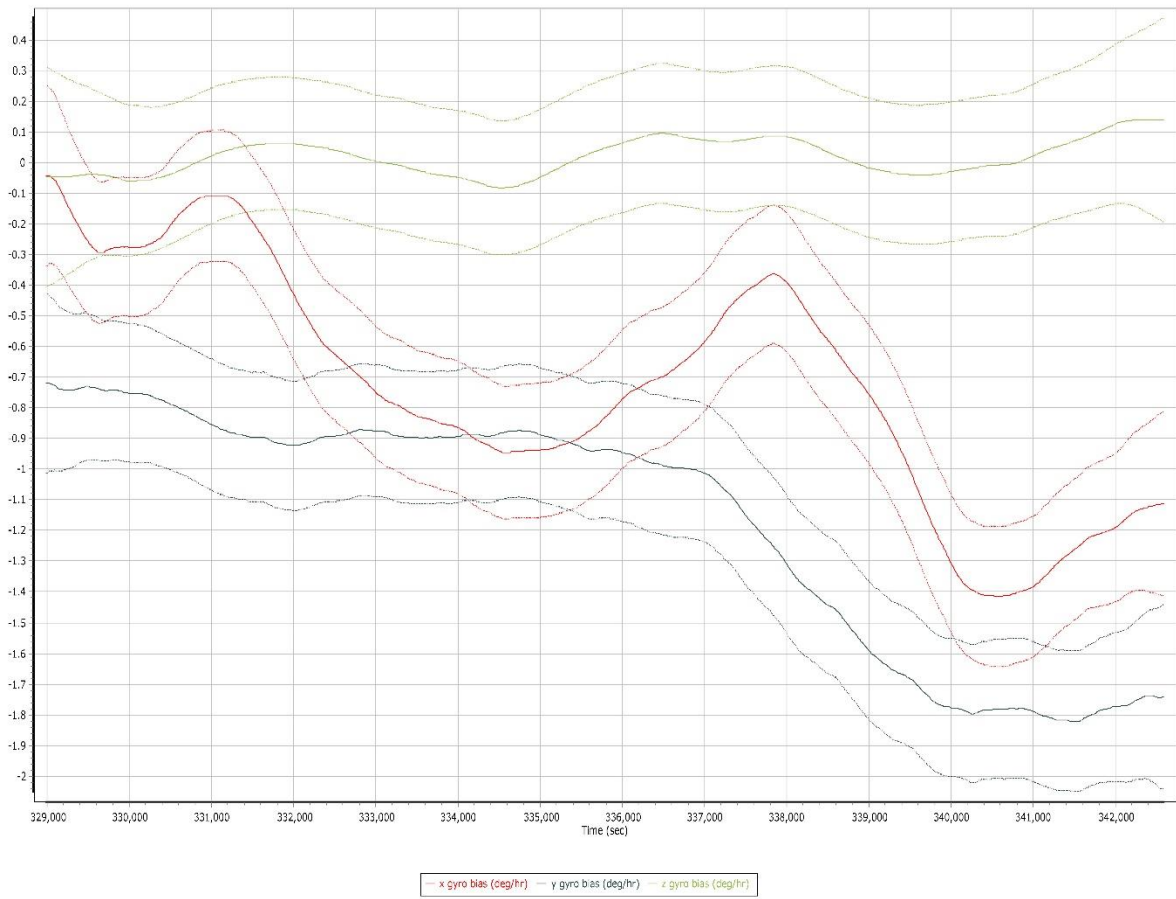


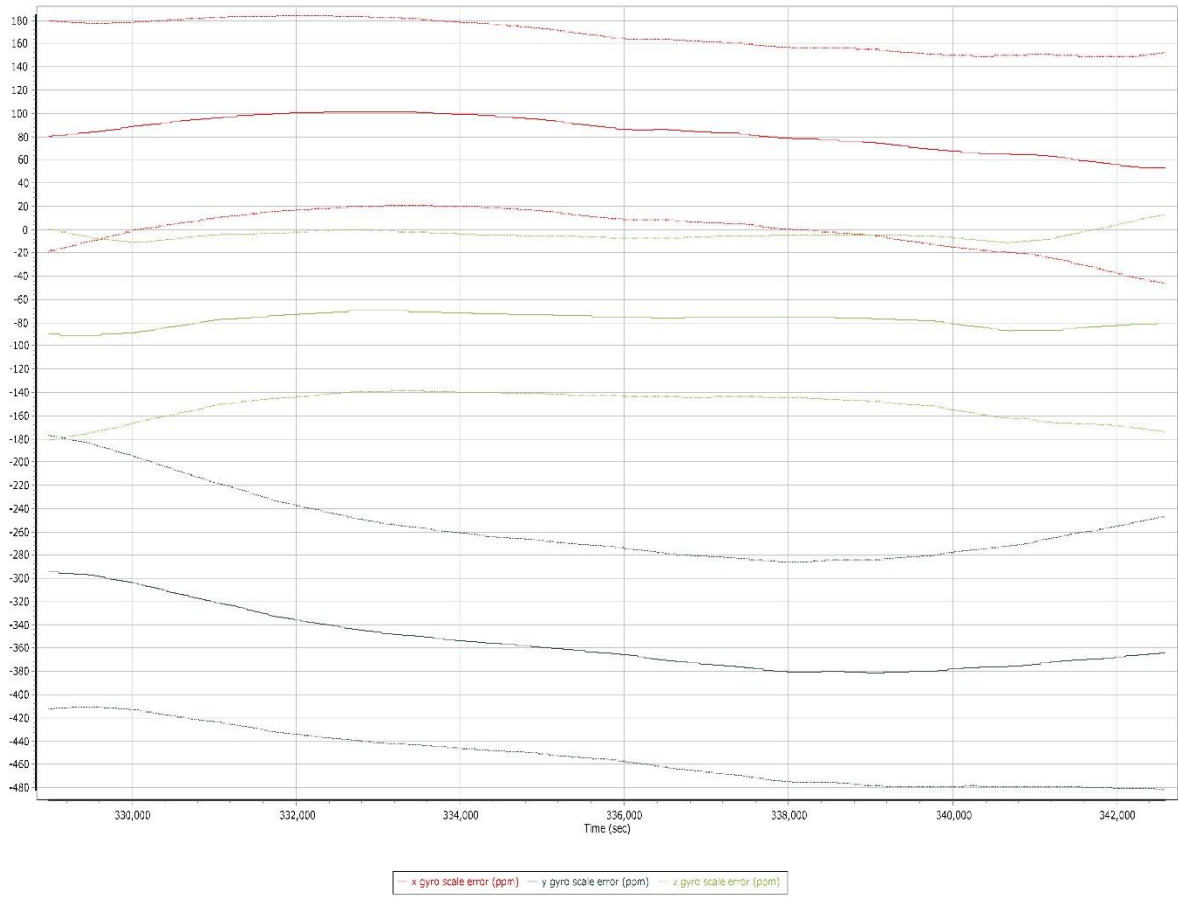




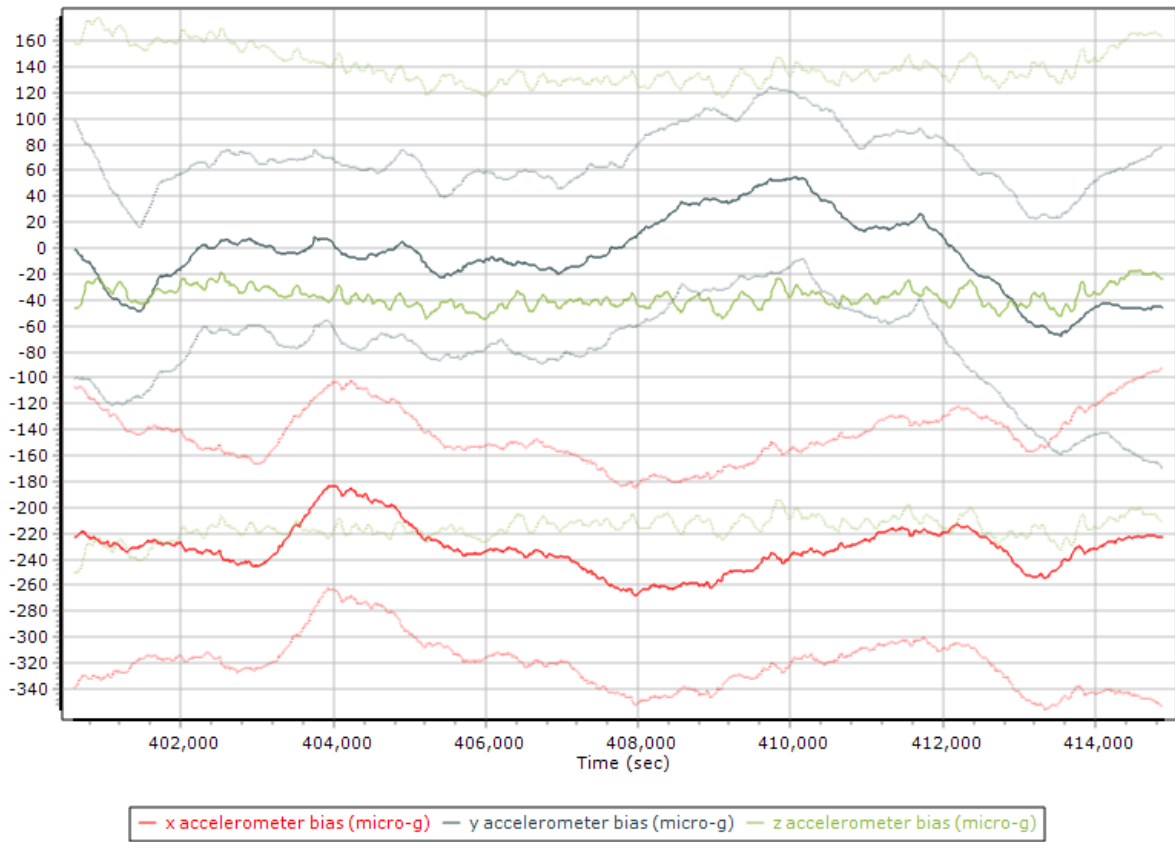


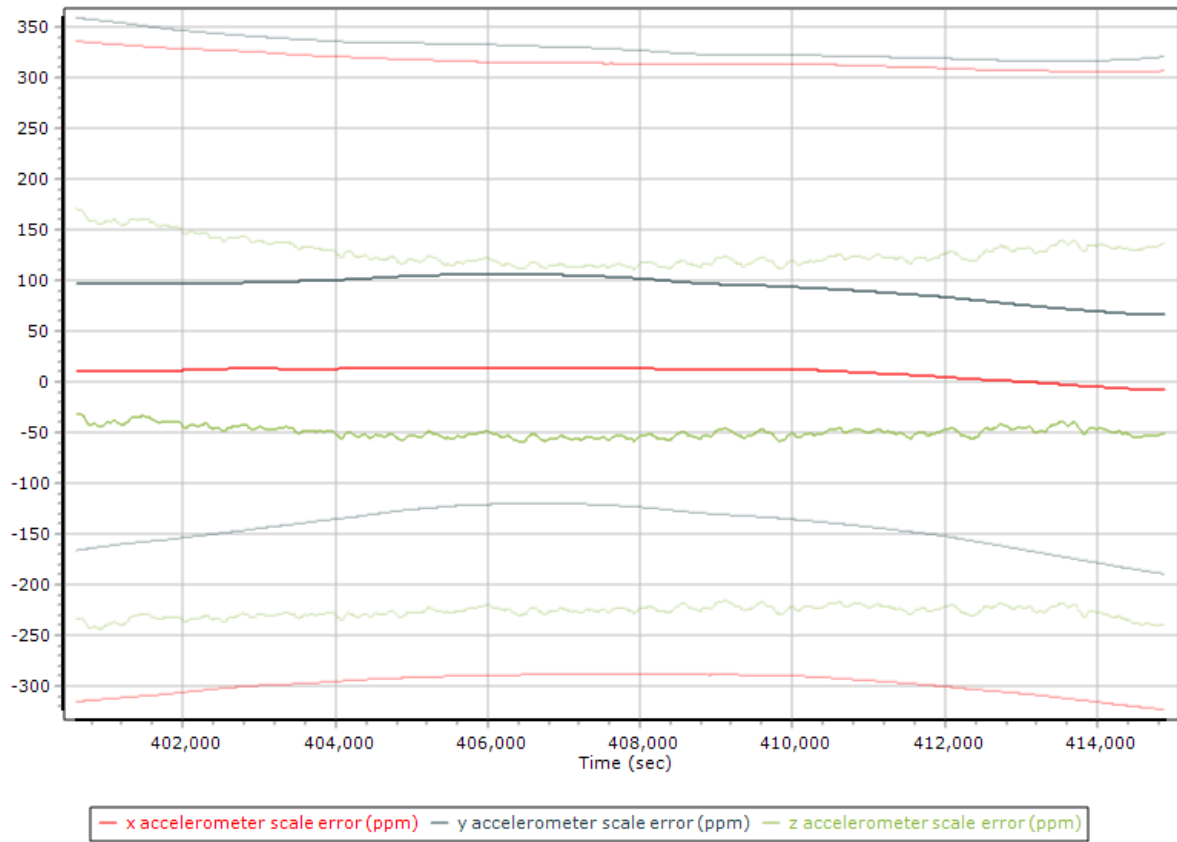


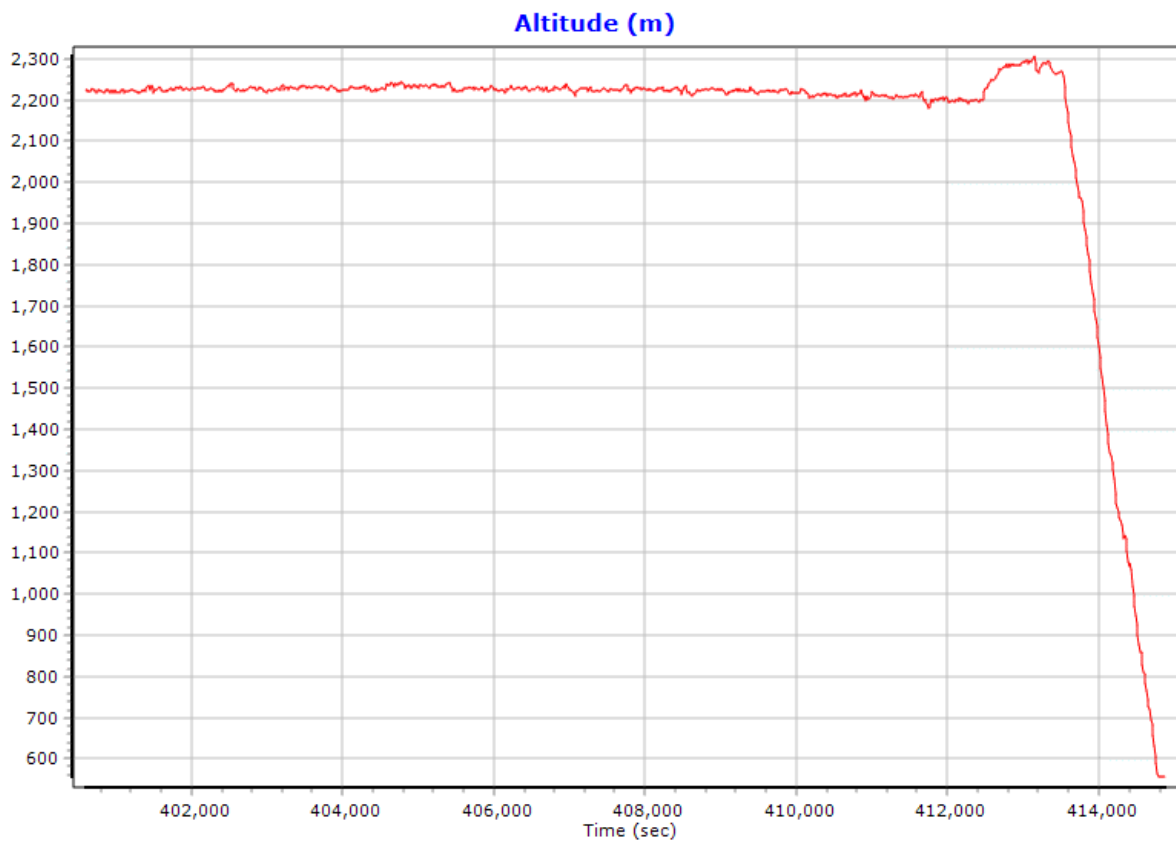


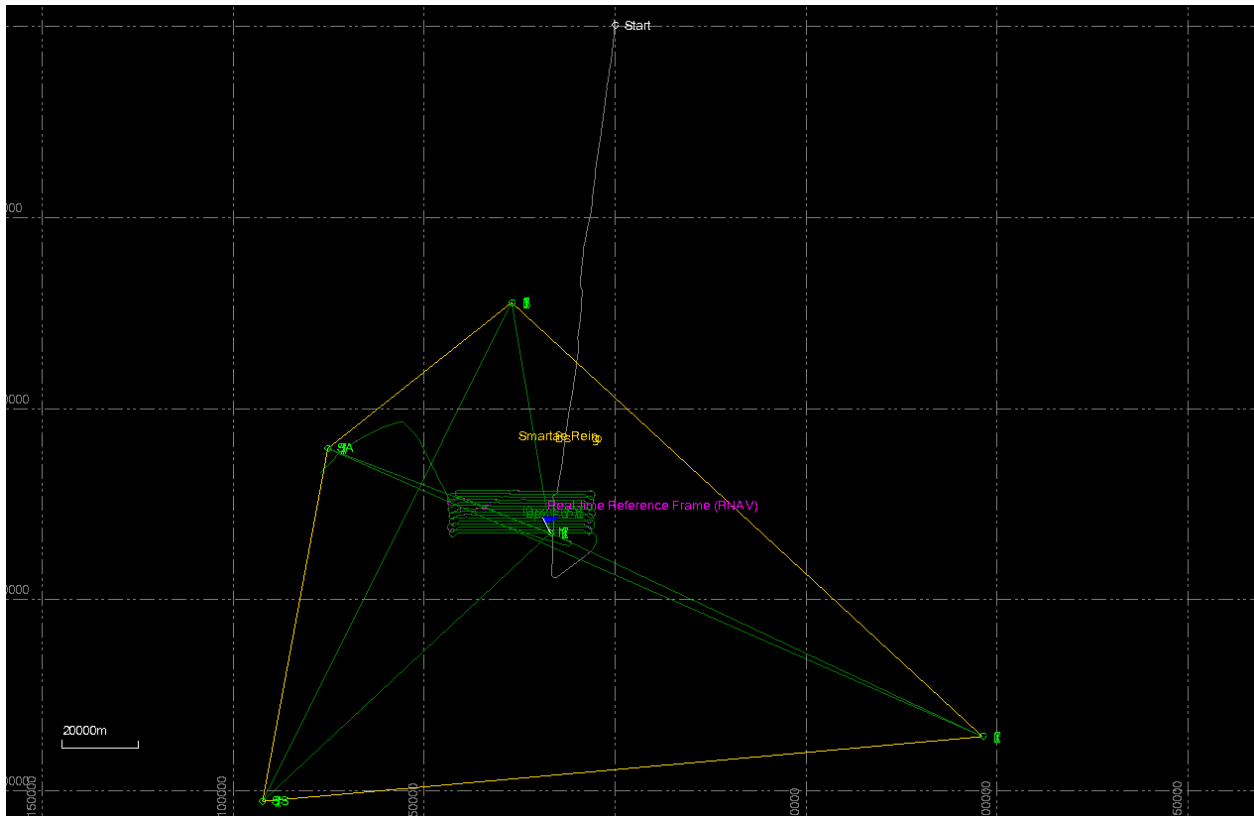
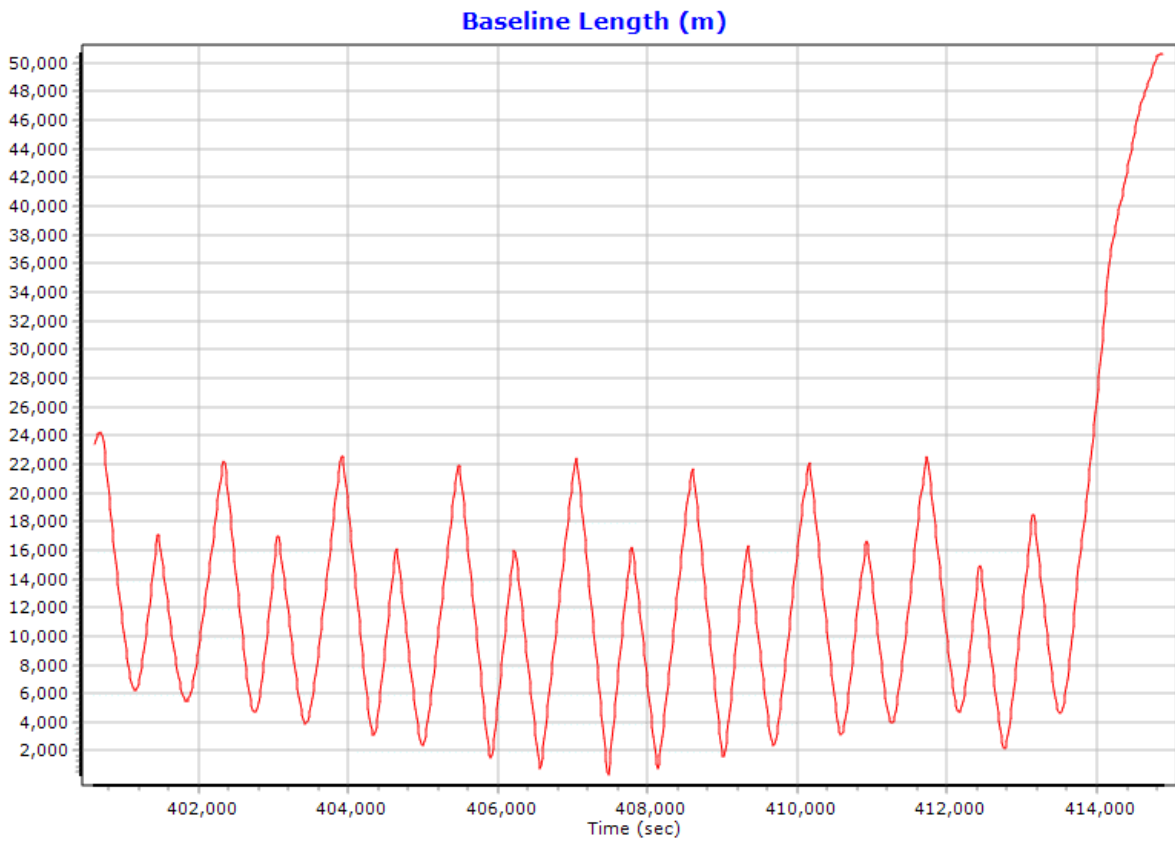


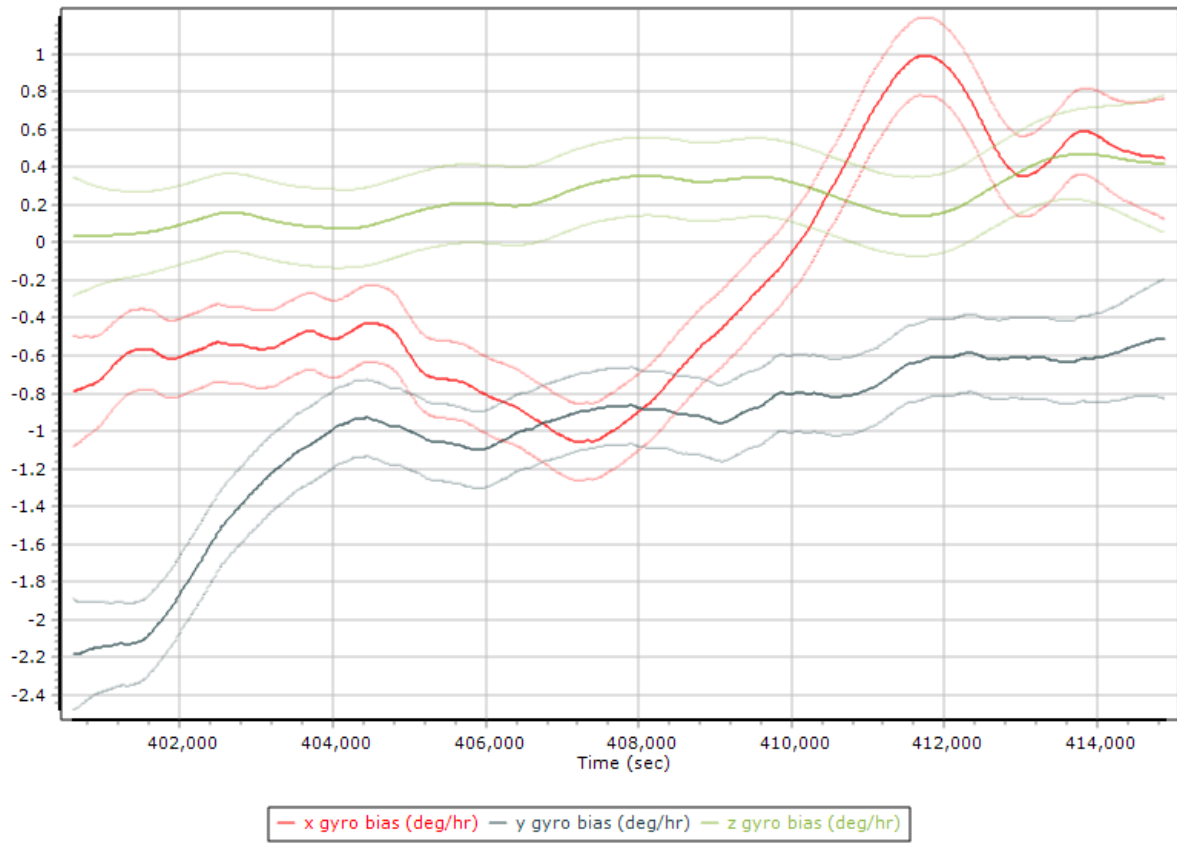
CAU18067A

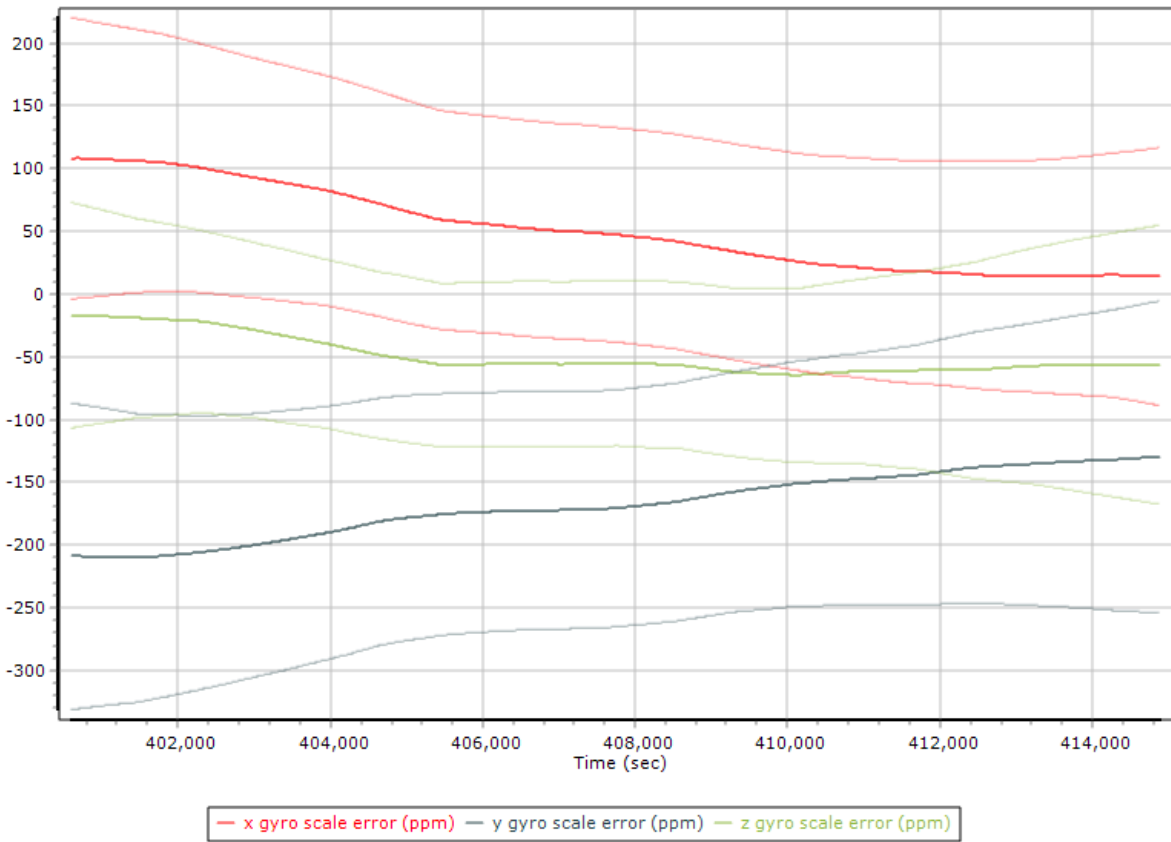












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

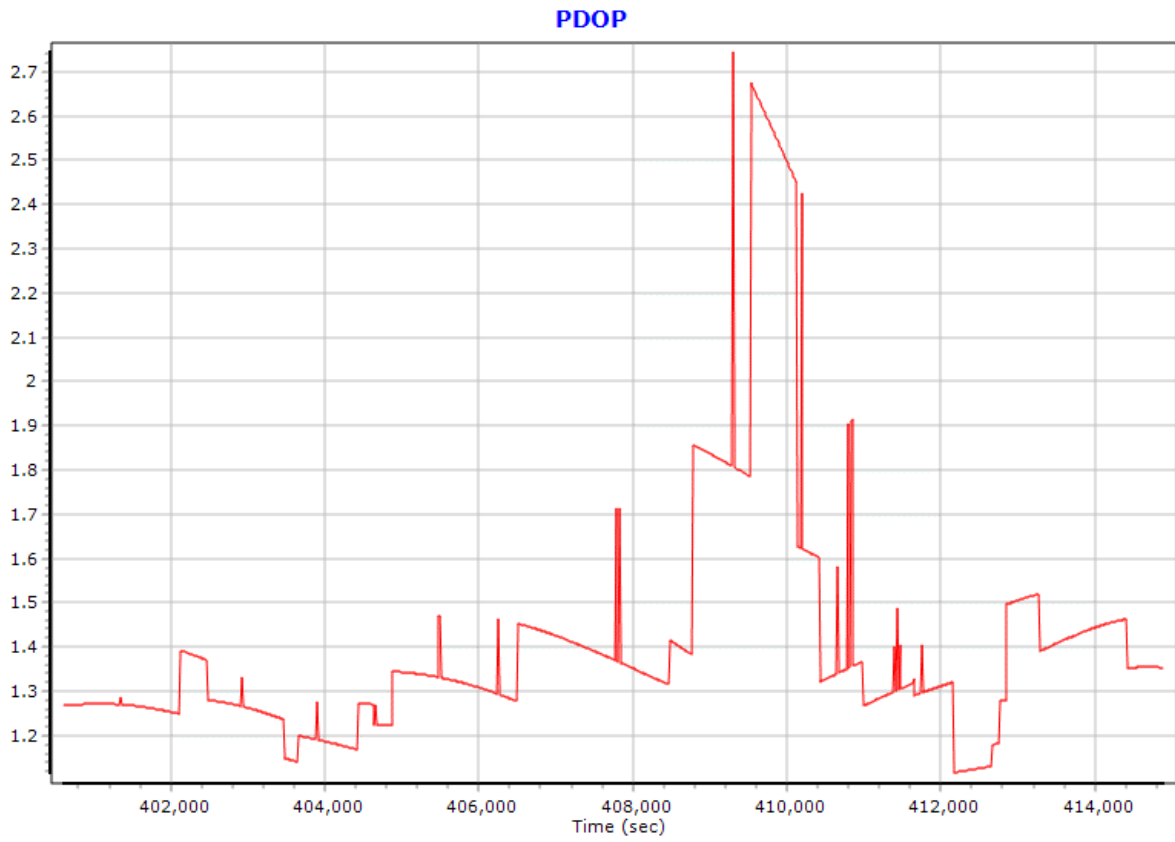
Aircraft to Reference Mounting Angles

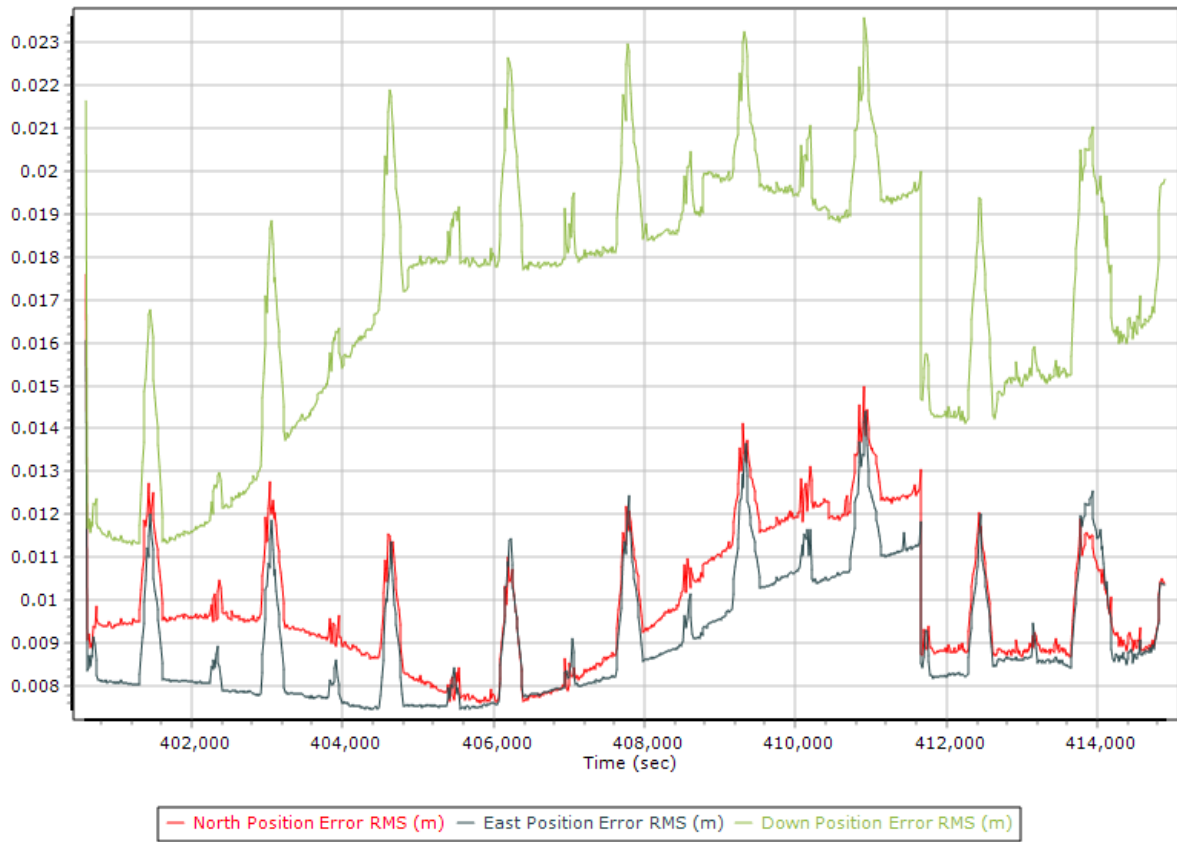
X:

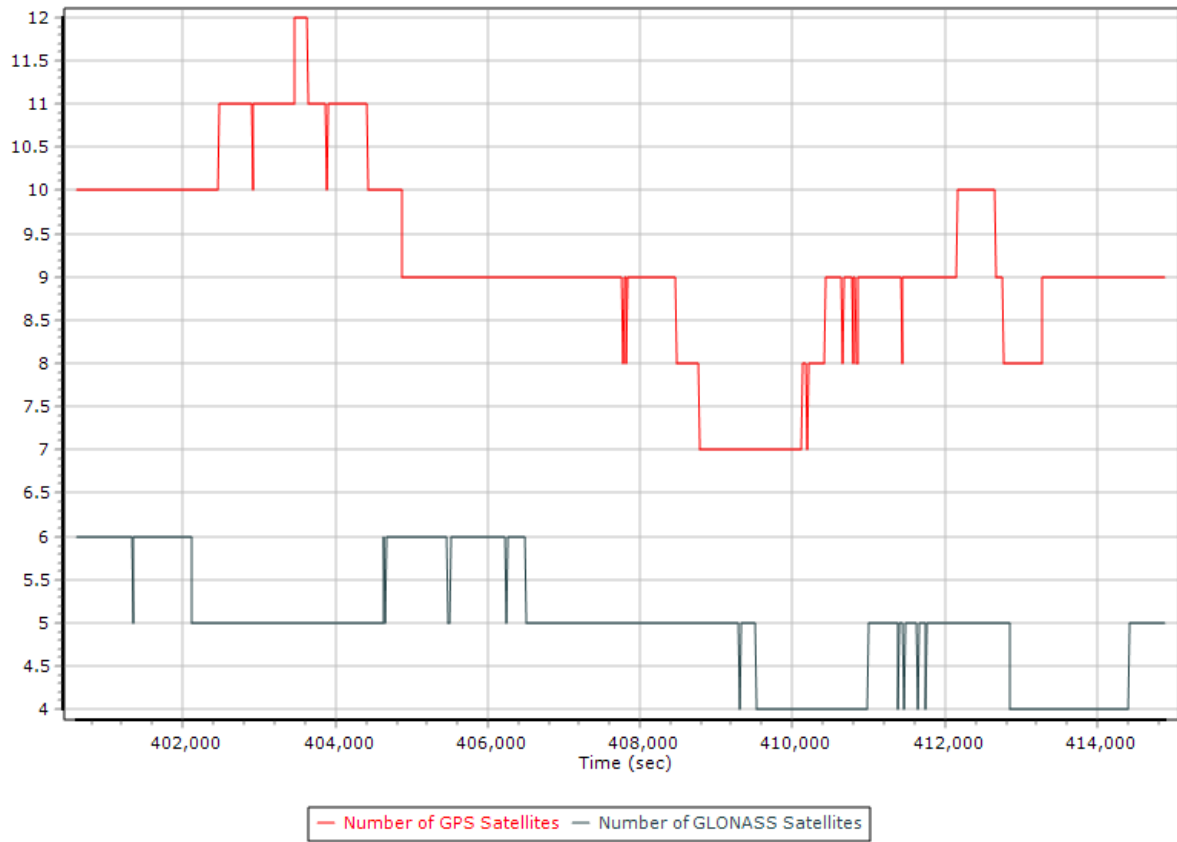
Y:

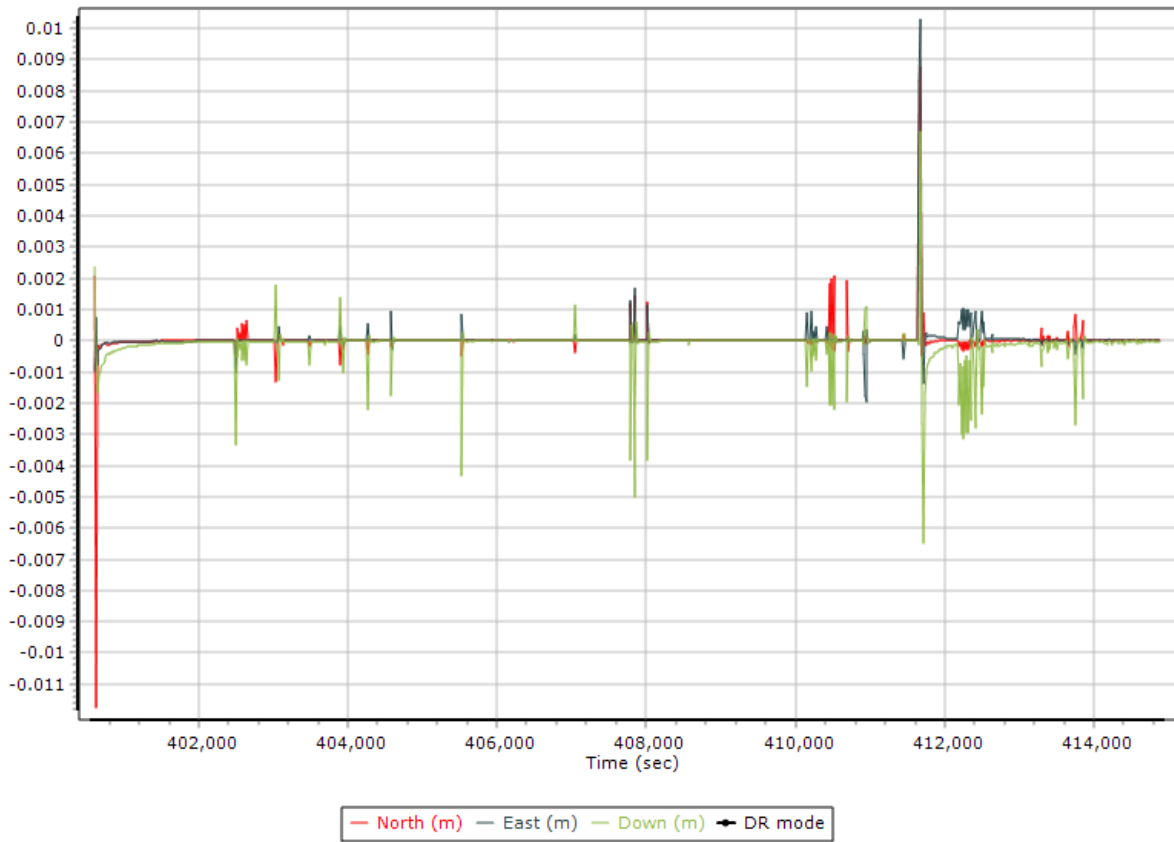
Z:

OK Cancel









Project Settings [X]

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

Timing

Start: 396283.000
 End: 414901.000
 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

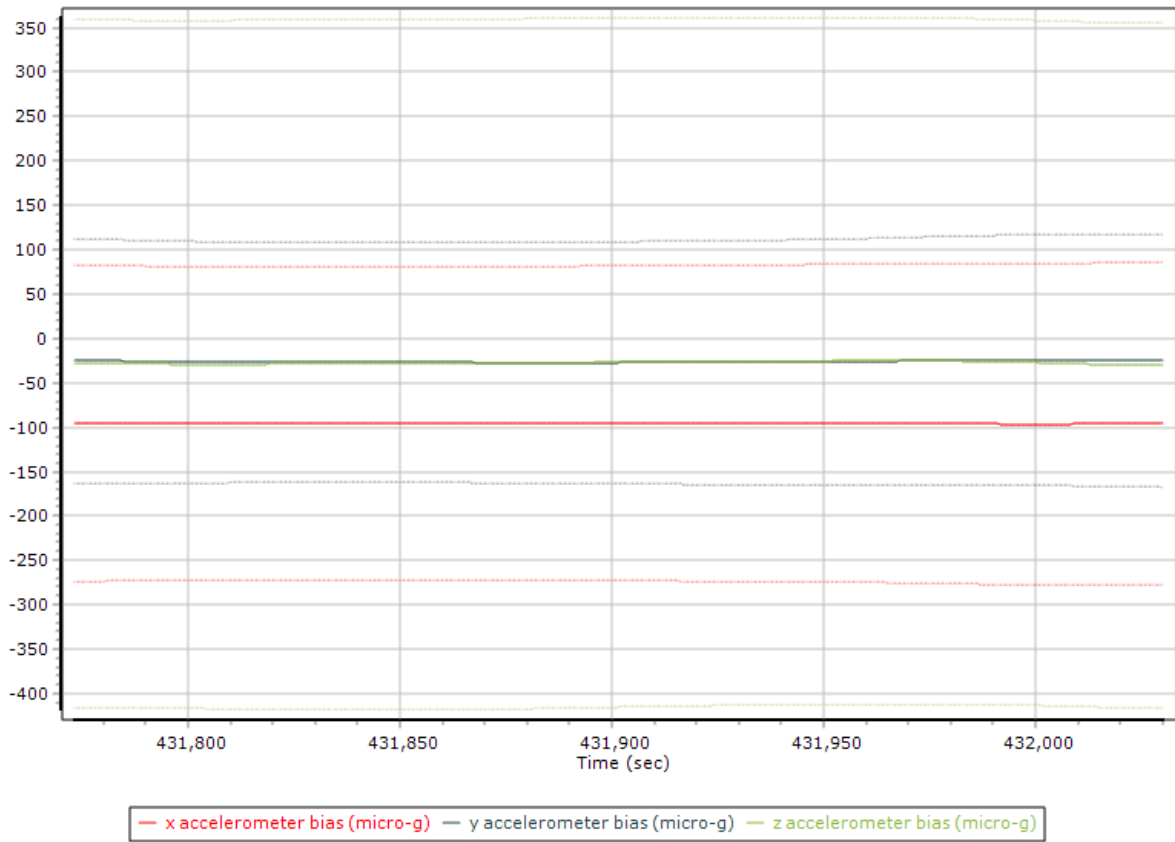
Processable Time Windows

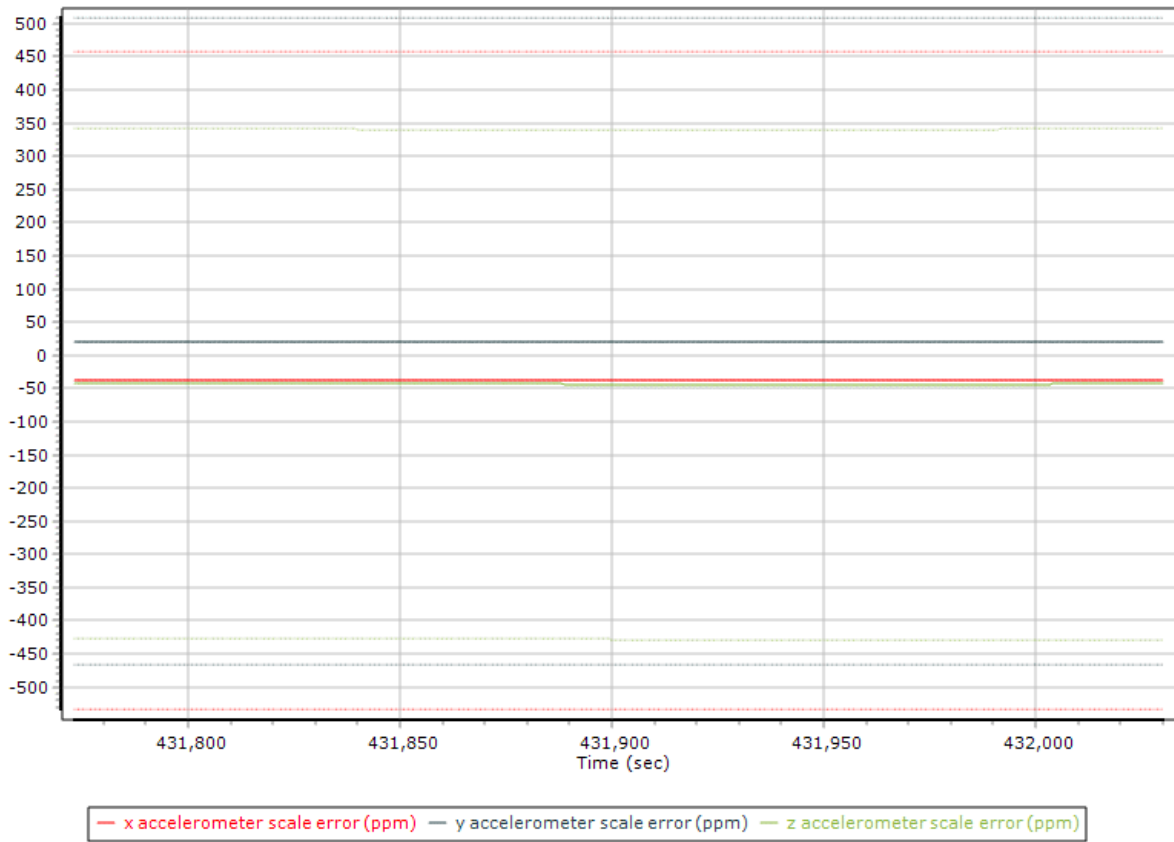
Start after launch Wait Time: 4.000 sec

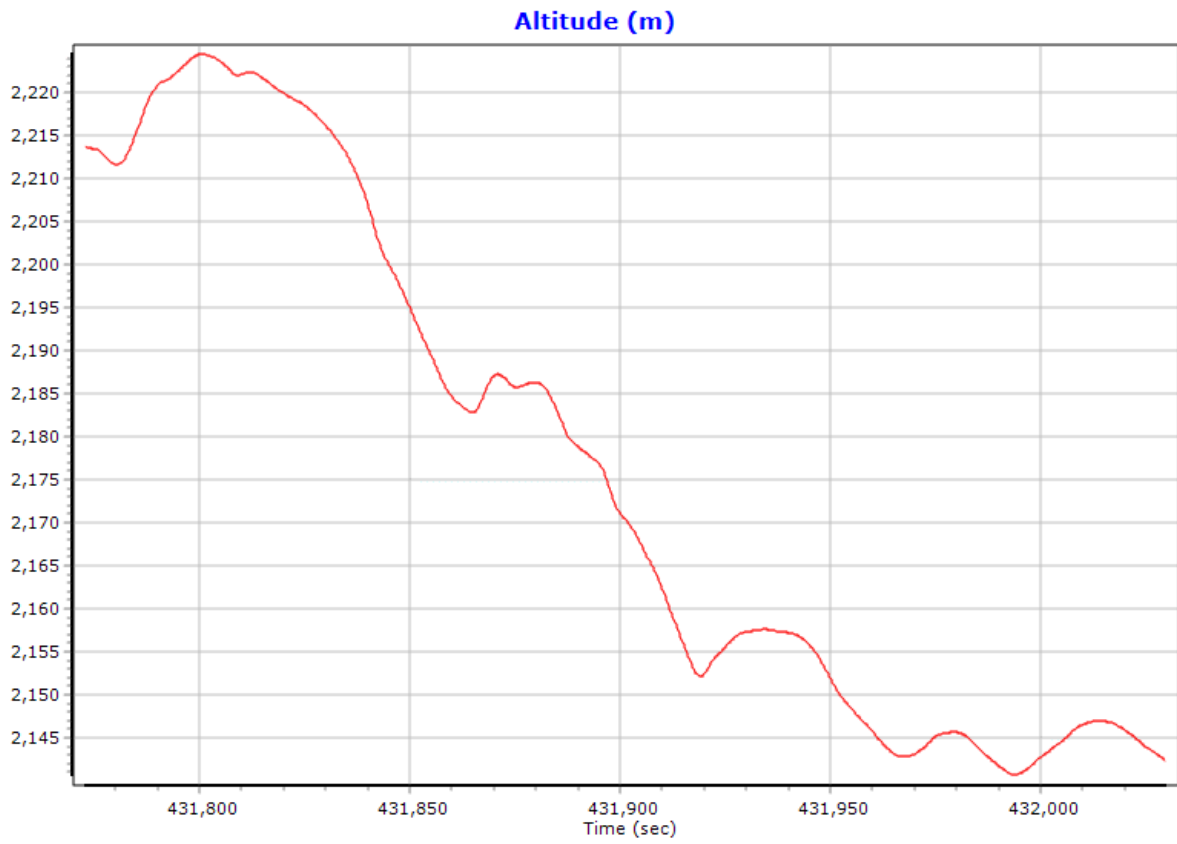
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	396283.000	414901.000	18618.000	End of file

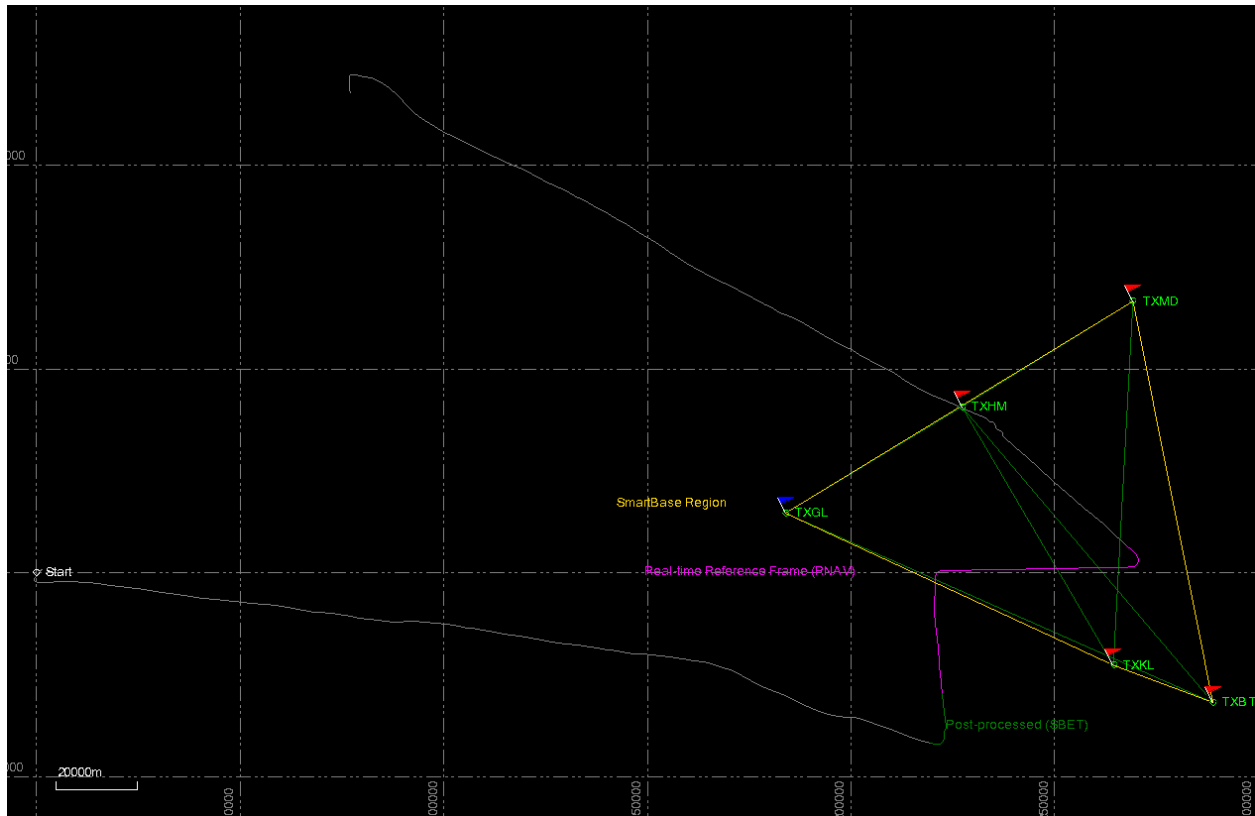
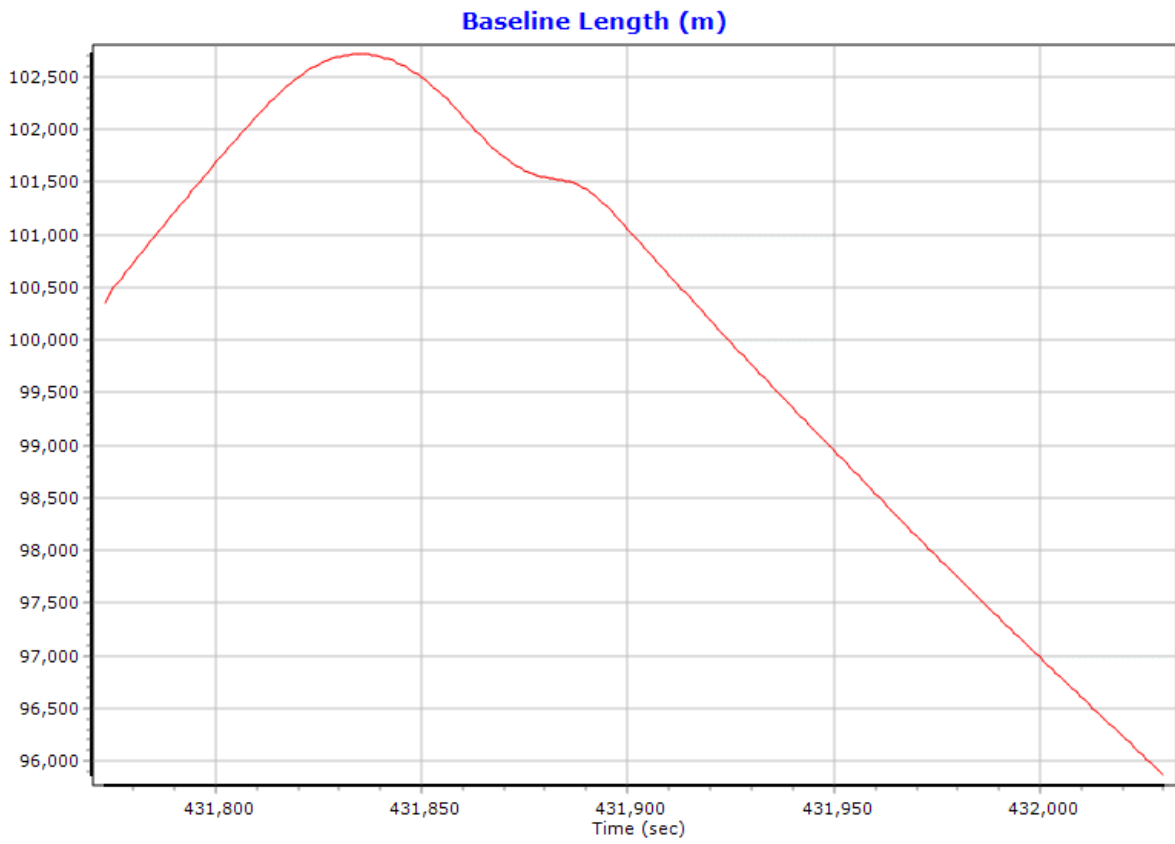
OK Cancel

CAU18067B

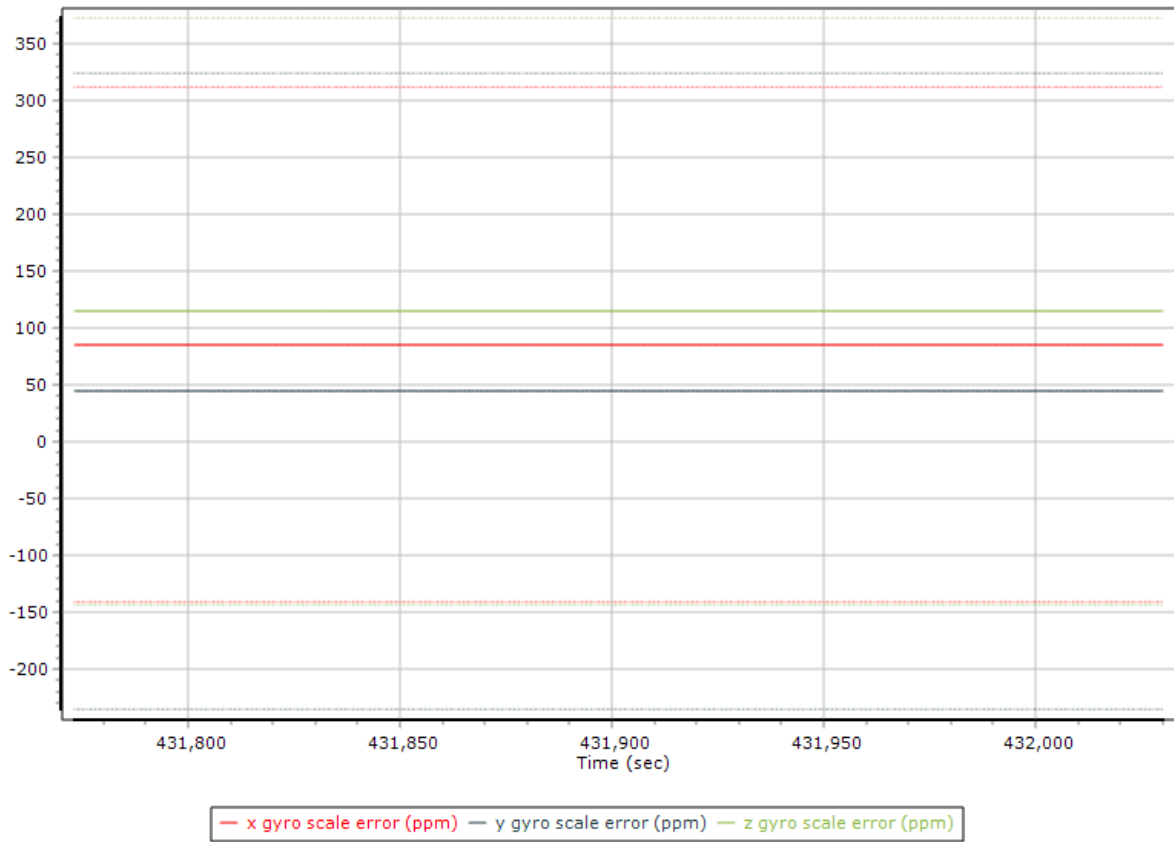












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation: (Selected)

<3cm 10cm 50cm 1m 10m

Aircraft to Reference Mounting Angles

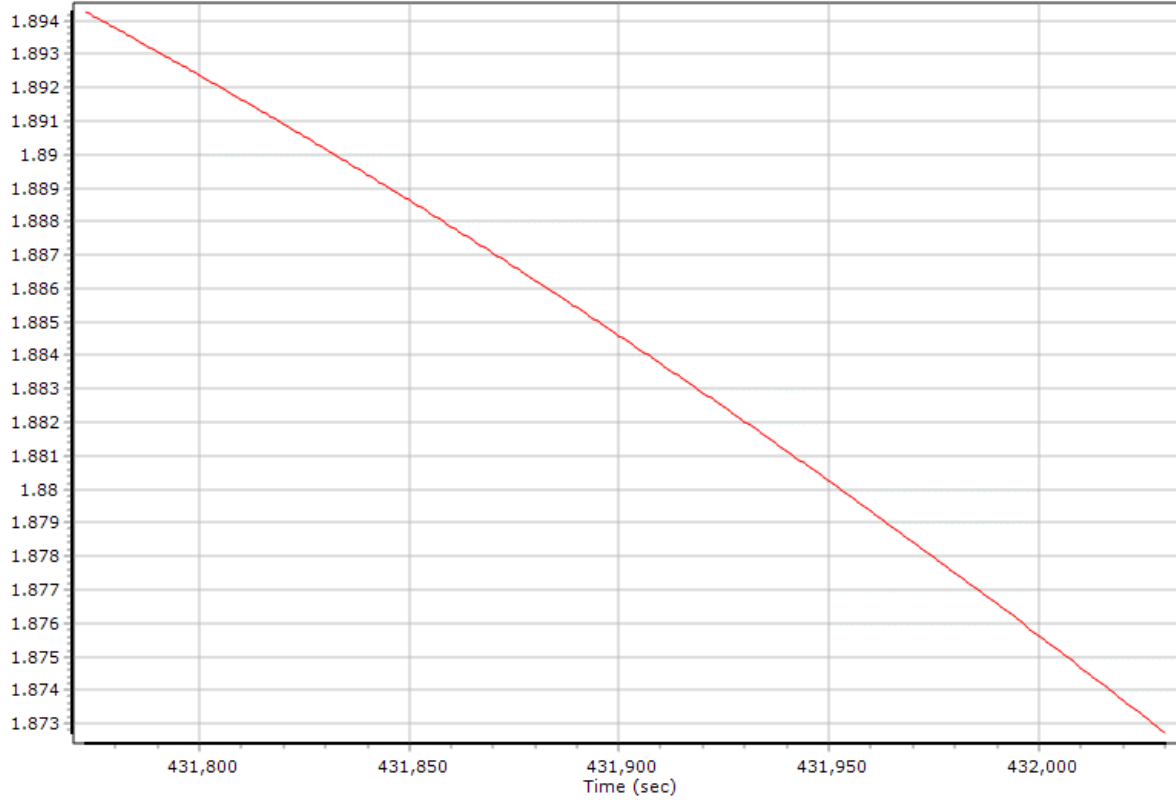
X:

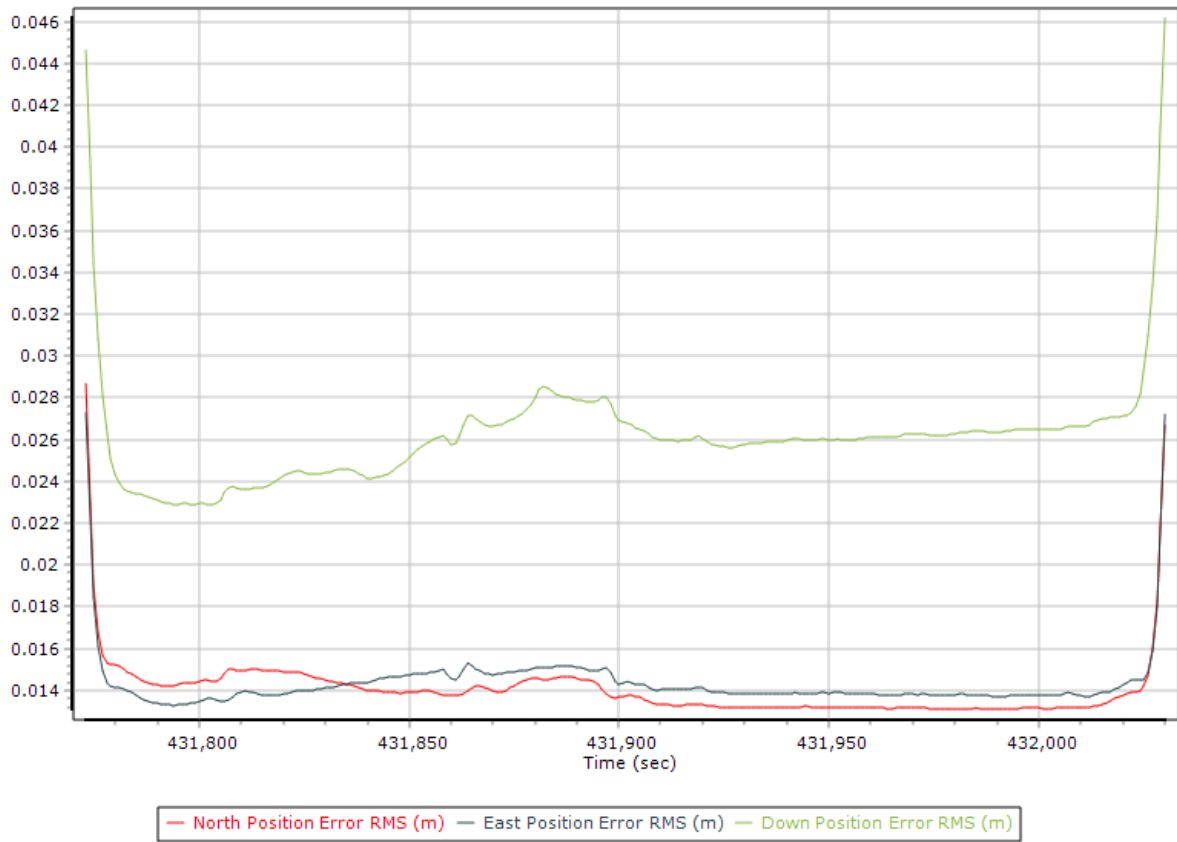
Y:

Z:

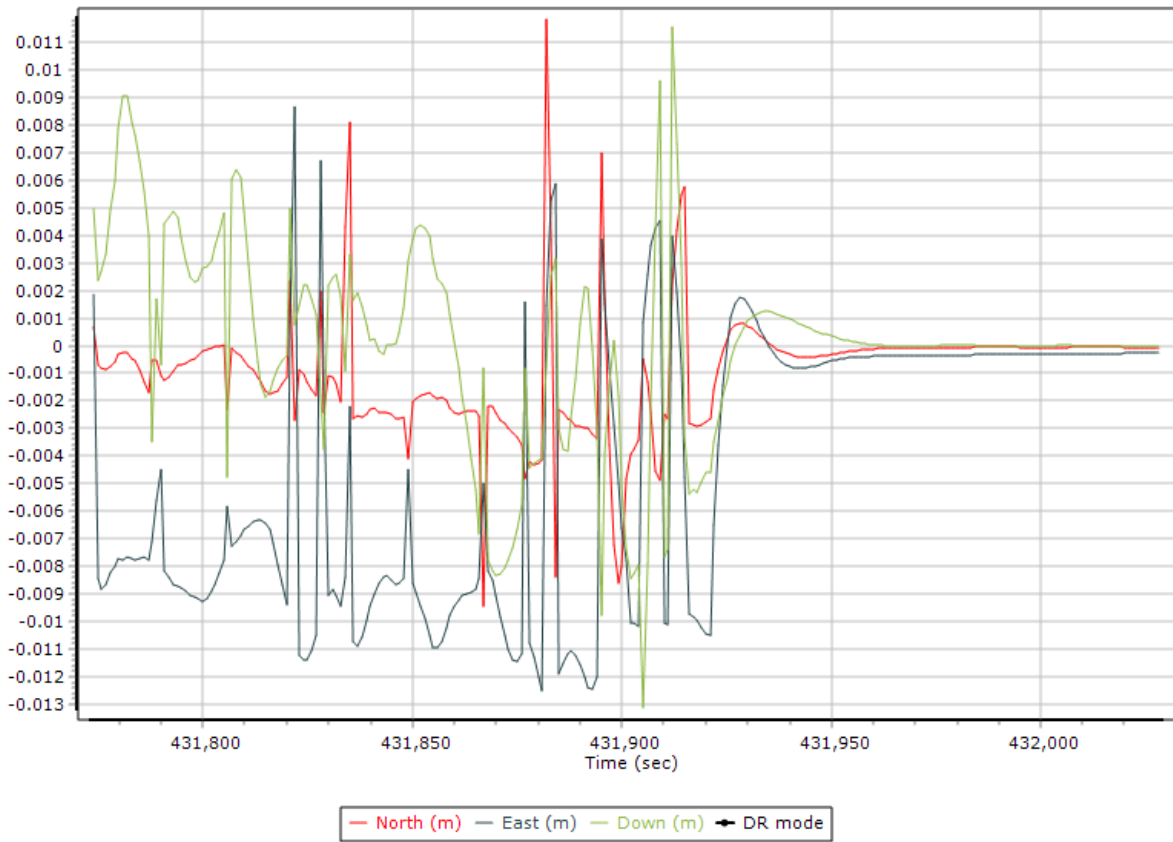
OK Cancel

PDOP









Project Settings [X]

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

Timing

Start: 426153.000
 End: 438261.000
 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

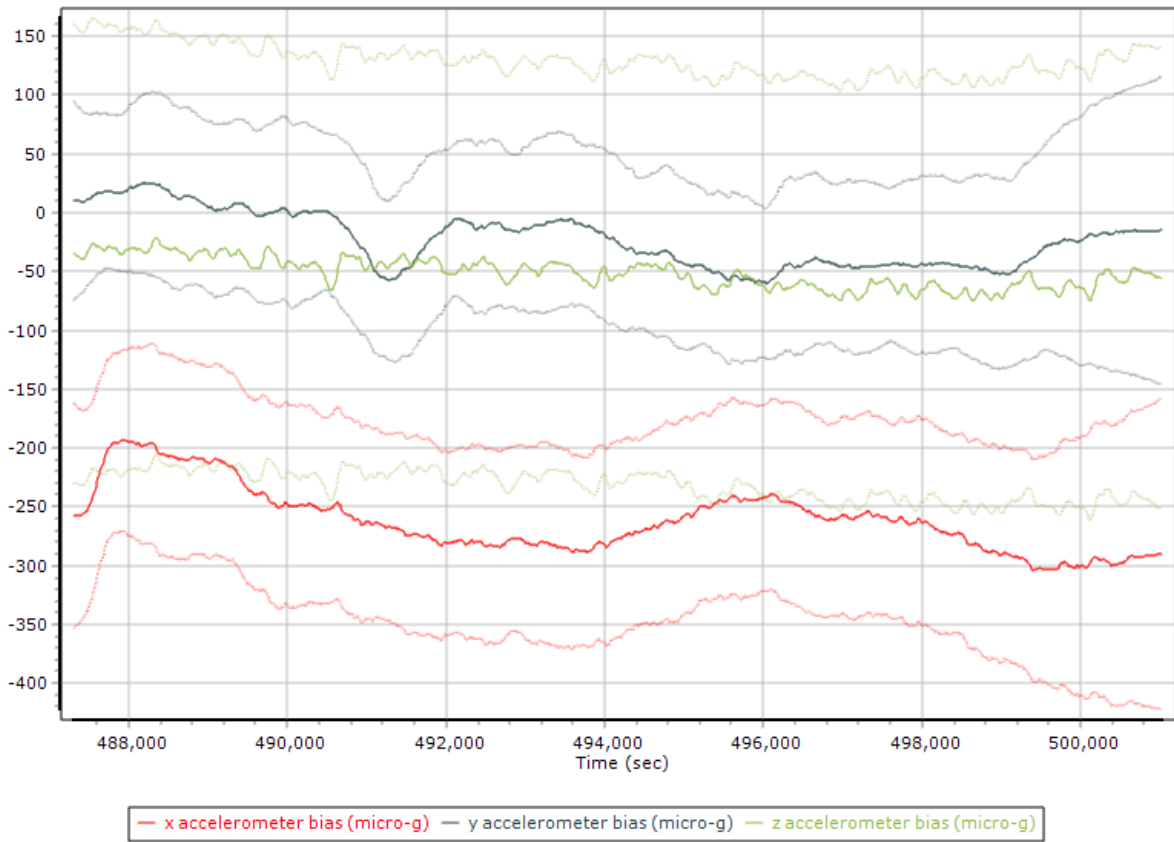
Processable Time Windows

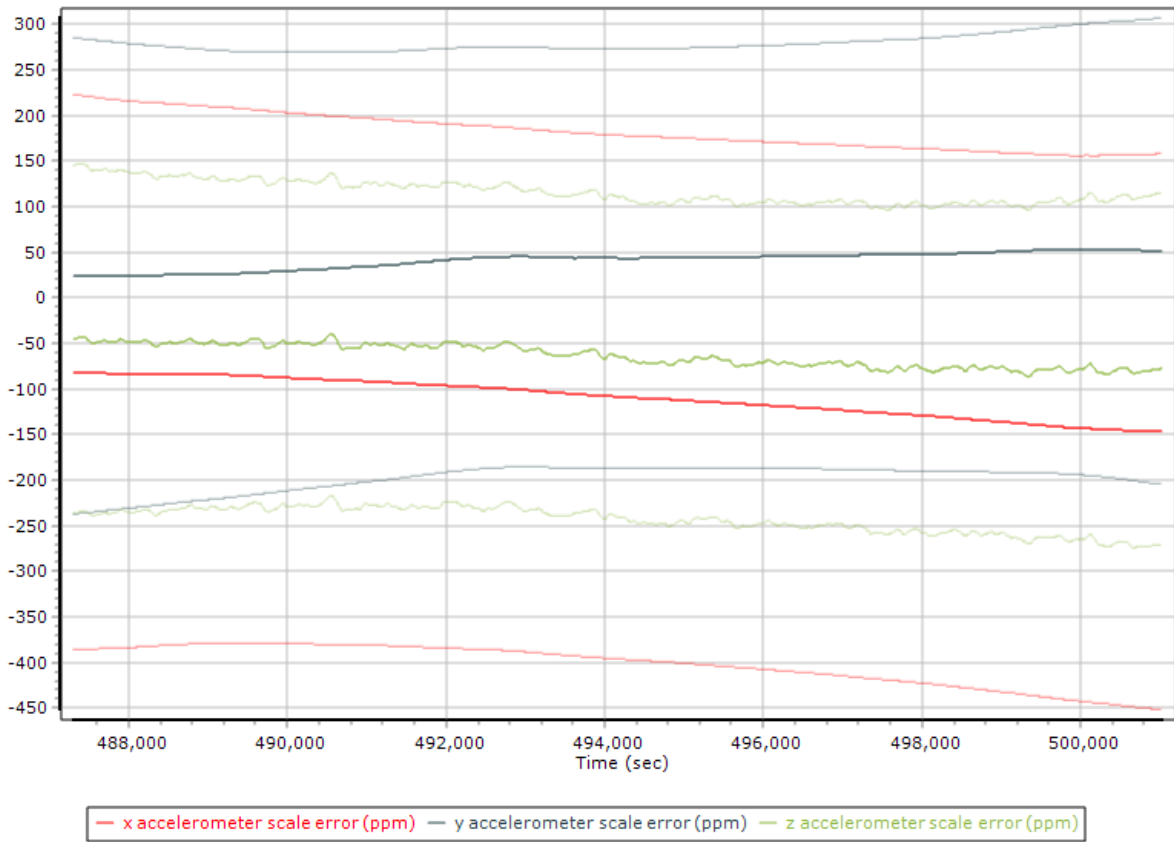
Start after launch Wait Time: 4.000 sec

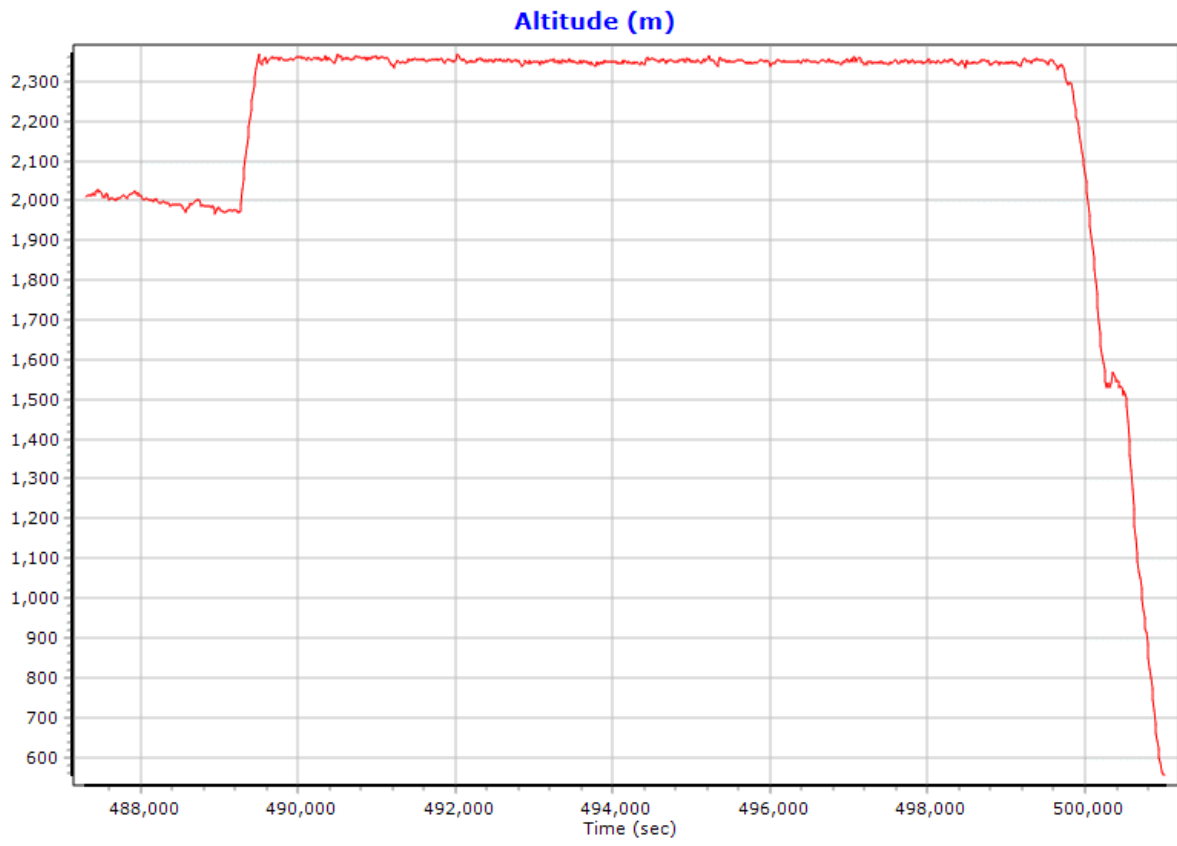
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	426153.000	438261.000	12108.000	End of file

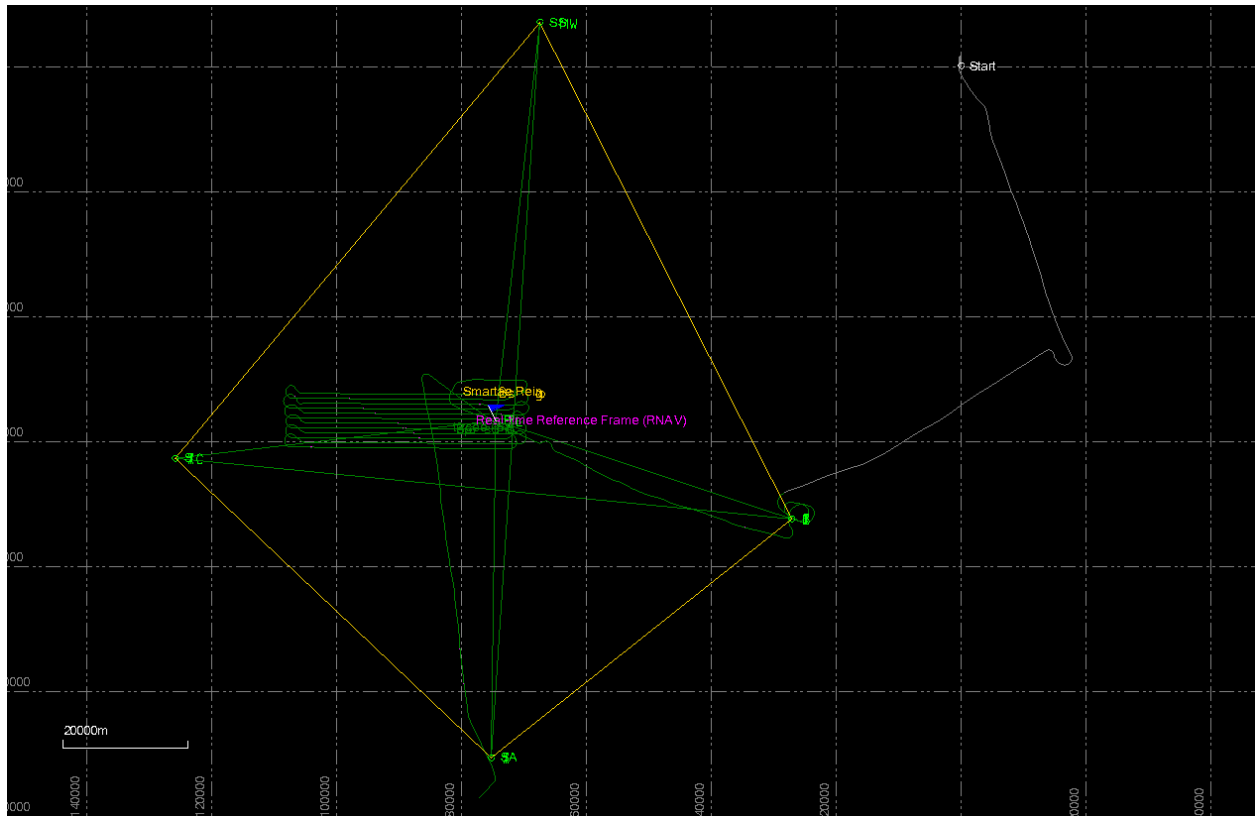
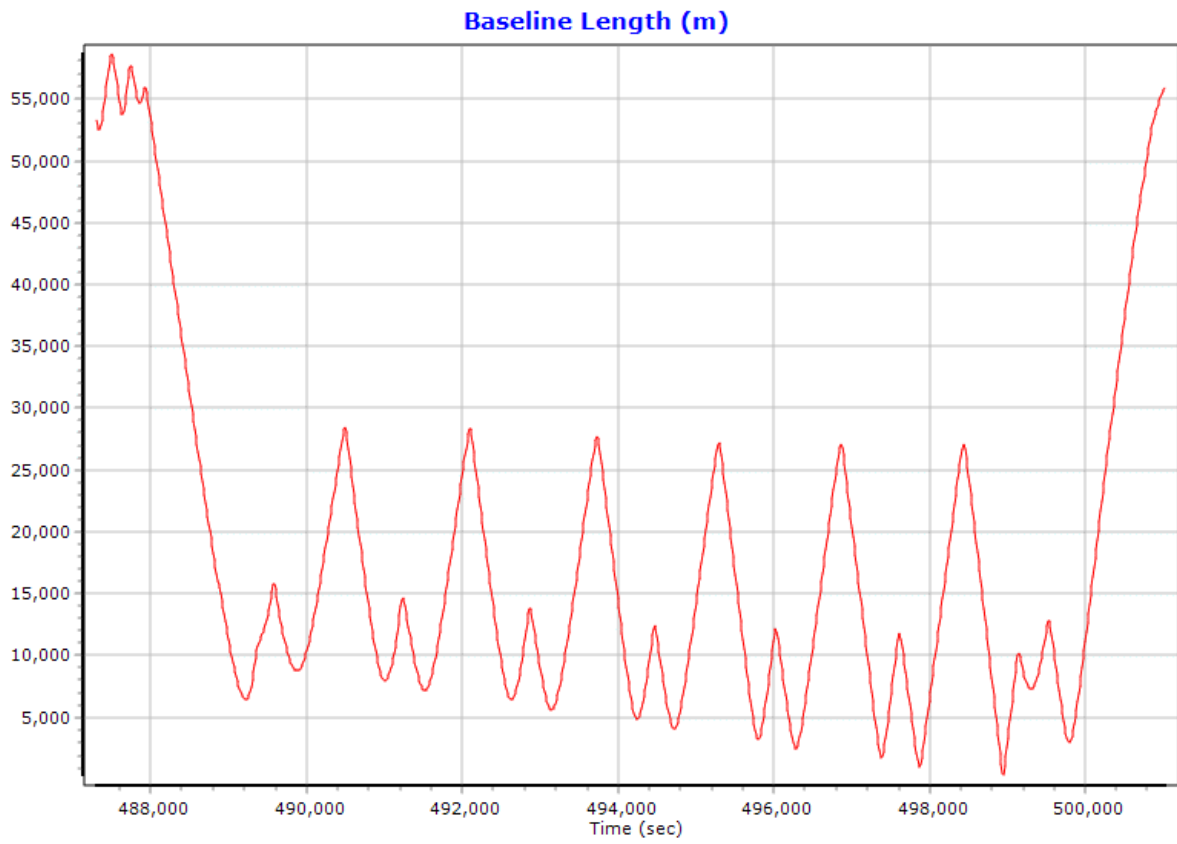
OK Cancel

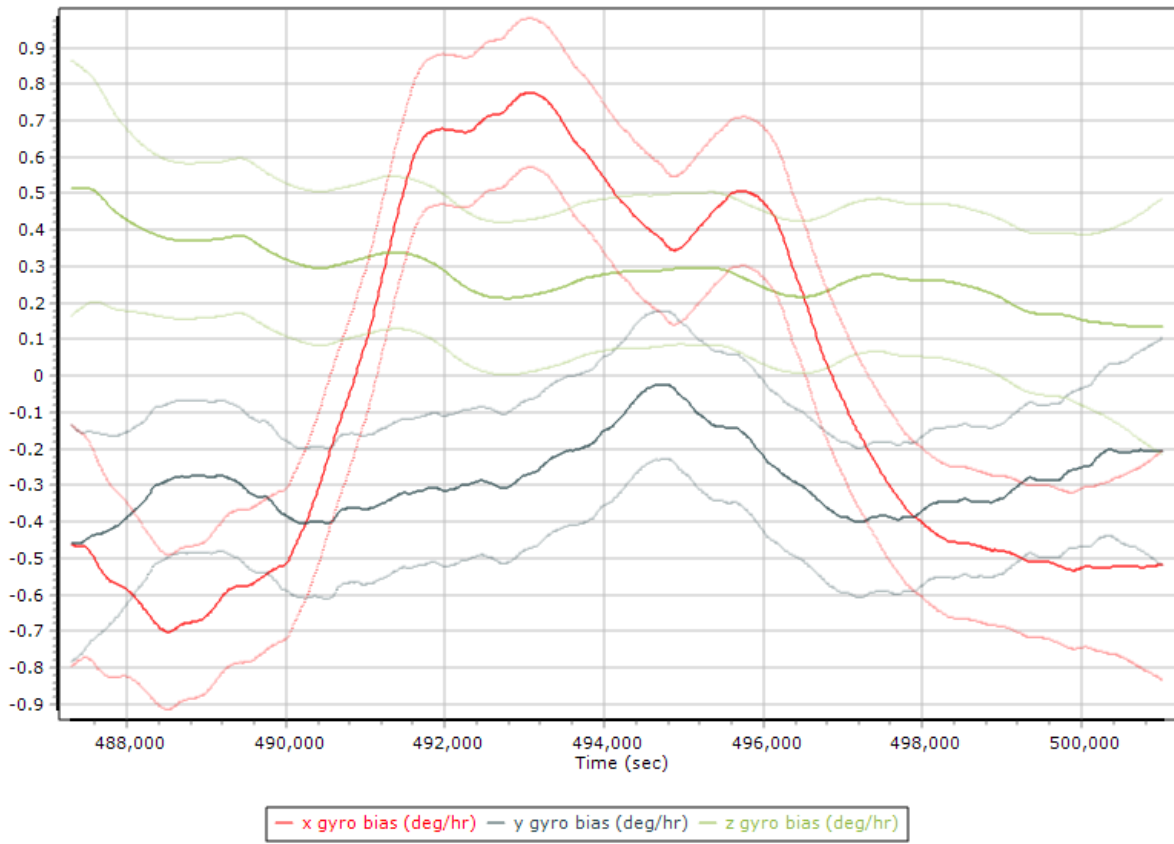
CAU18068A

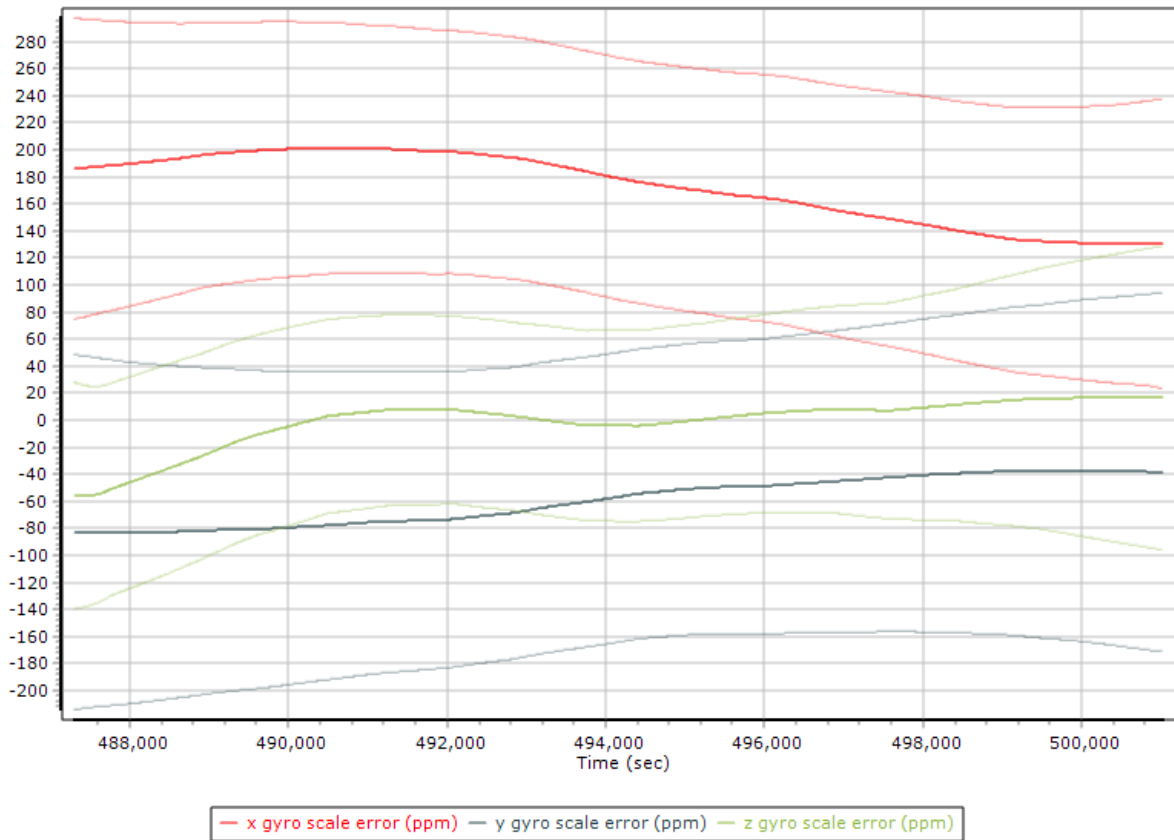












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

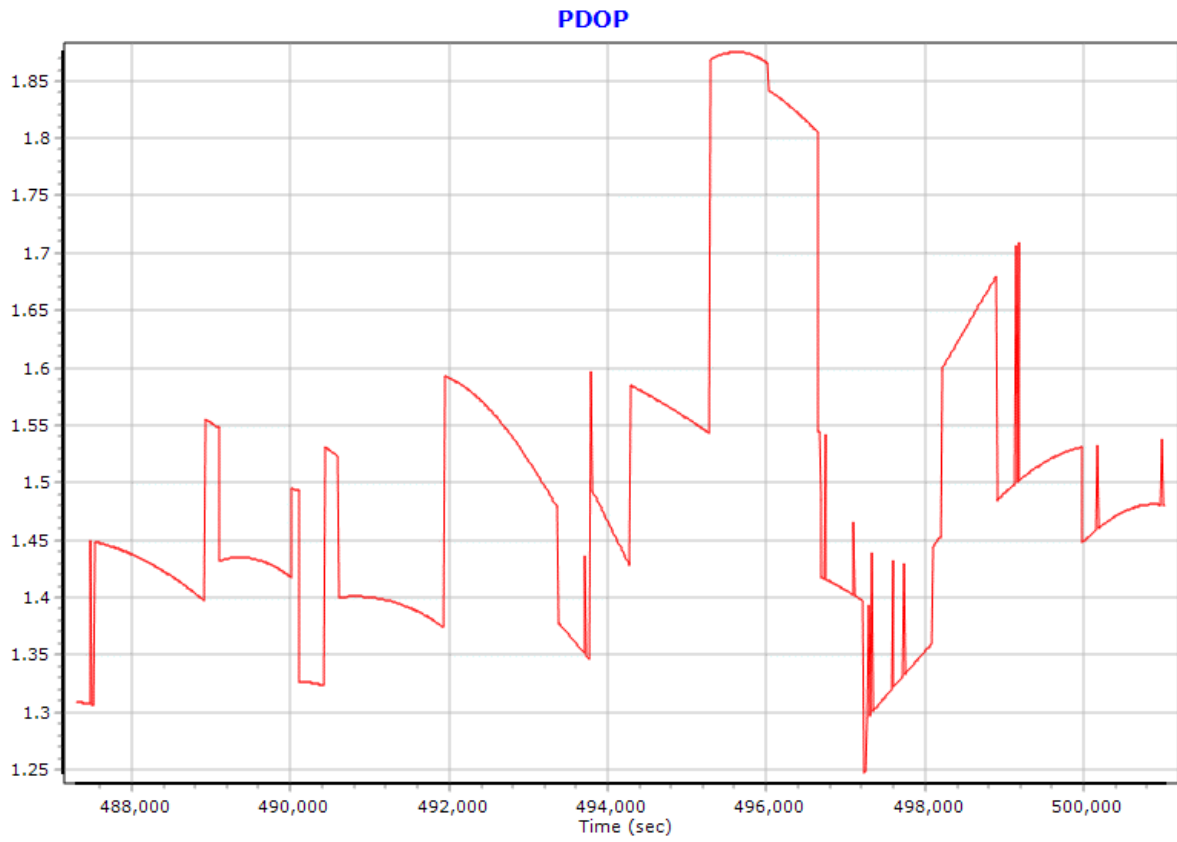
<3cm 10cm 50cm 1m 10m

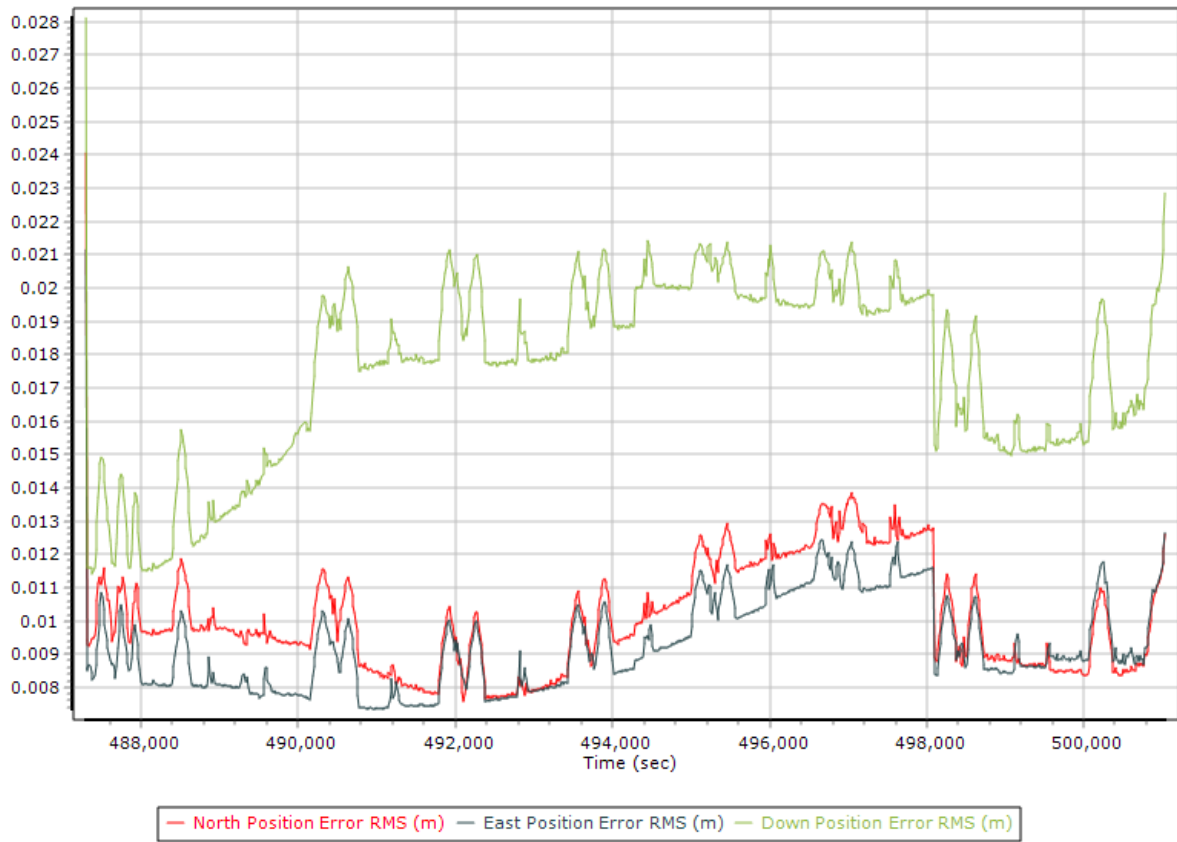
Aircraft to Reference Mounting Angles

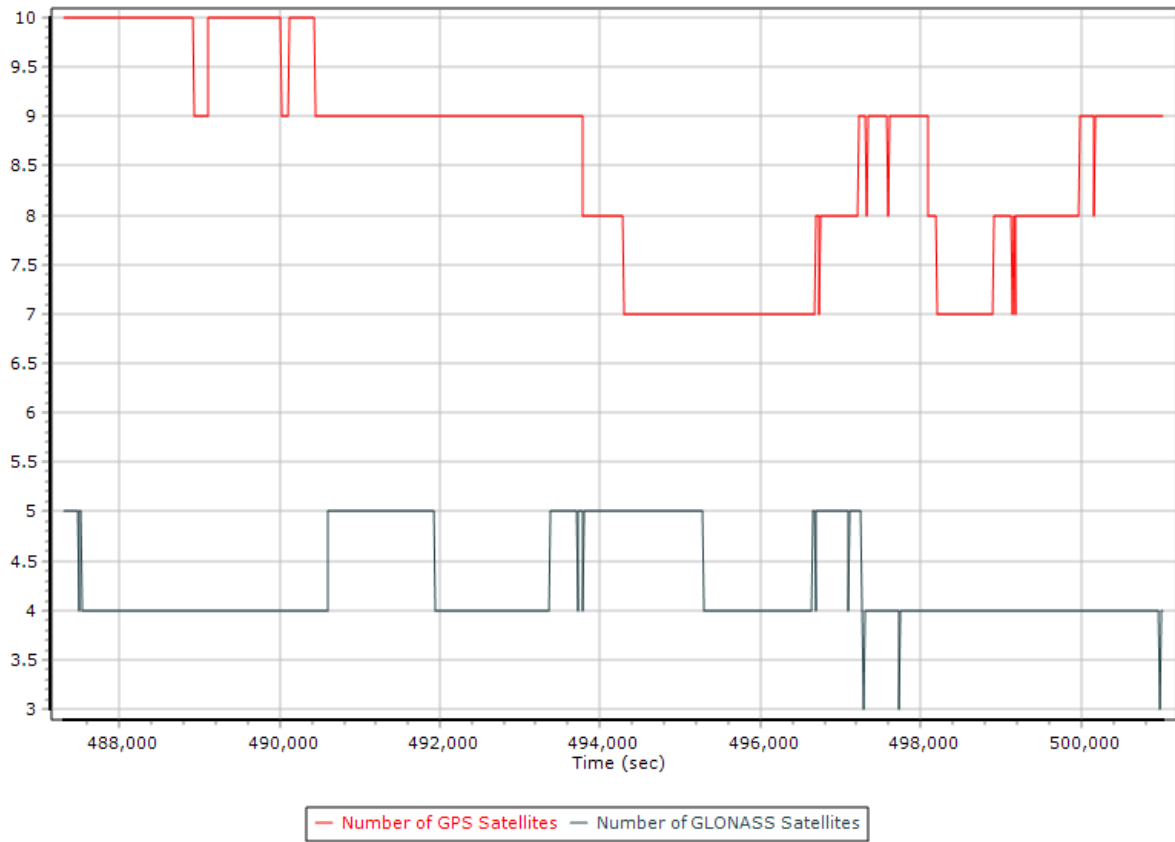
X:

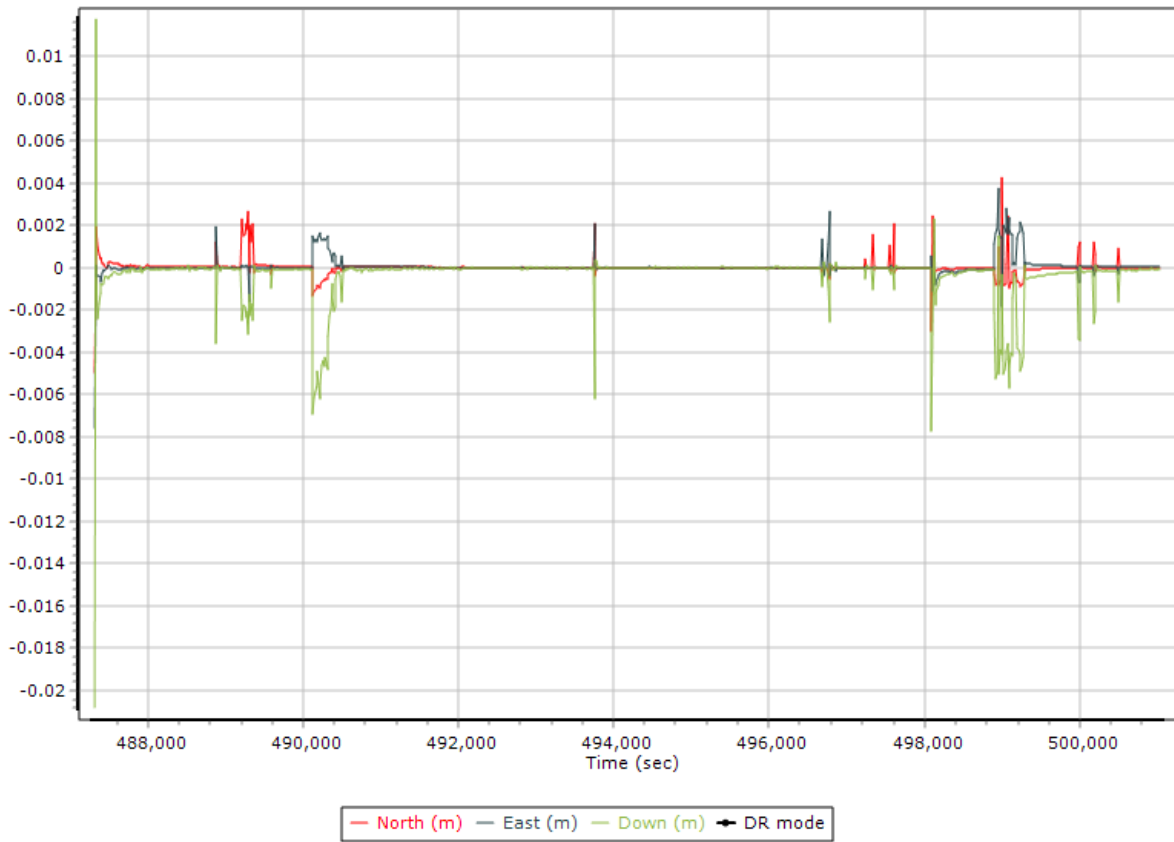
Y:

Z:









Project Settings [X]

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

Timing

Start: 483972.000
 End: 501046.000
 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

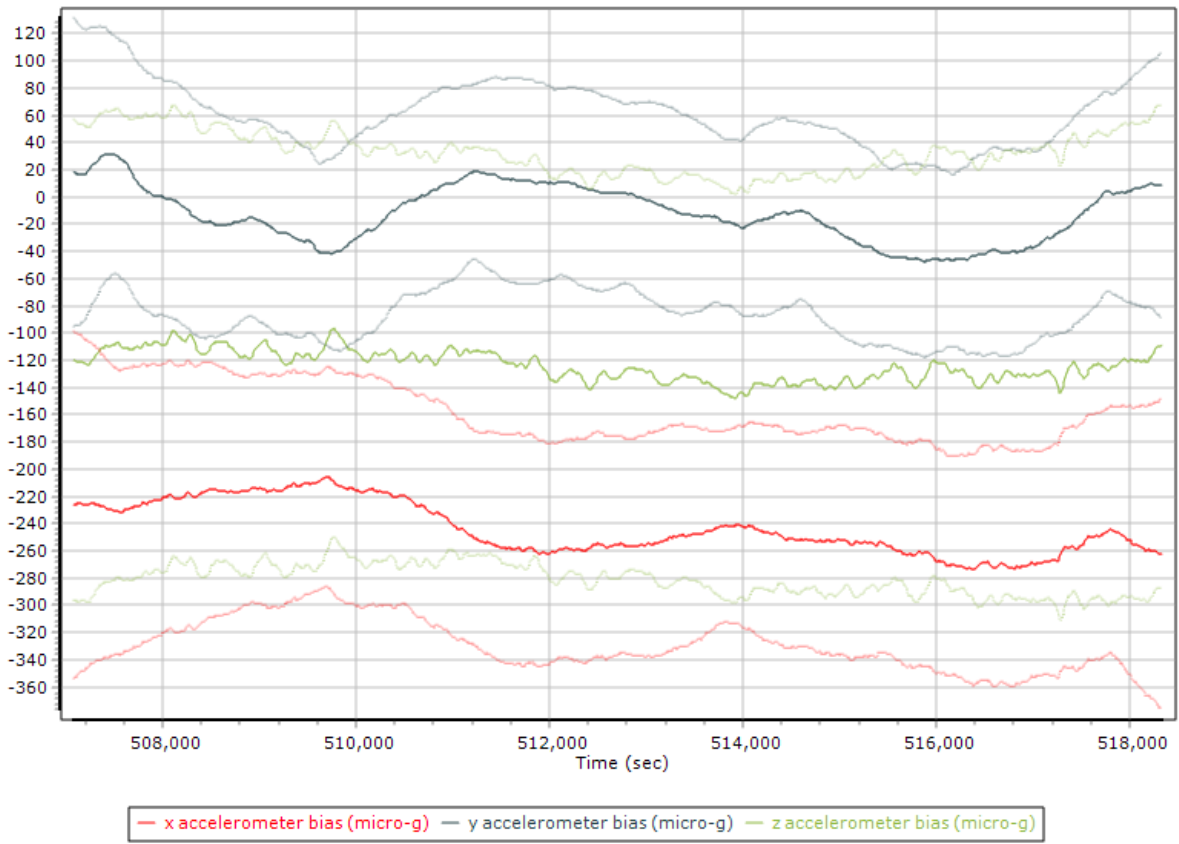
Processable Time Windows

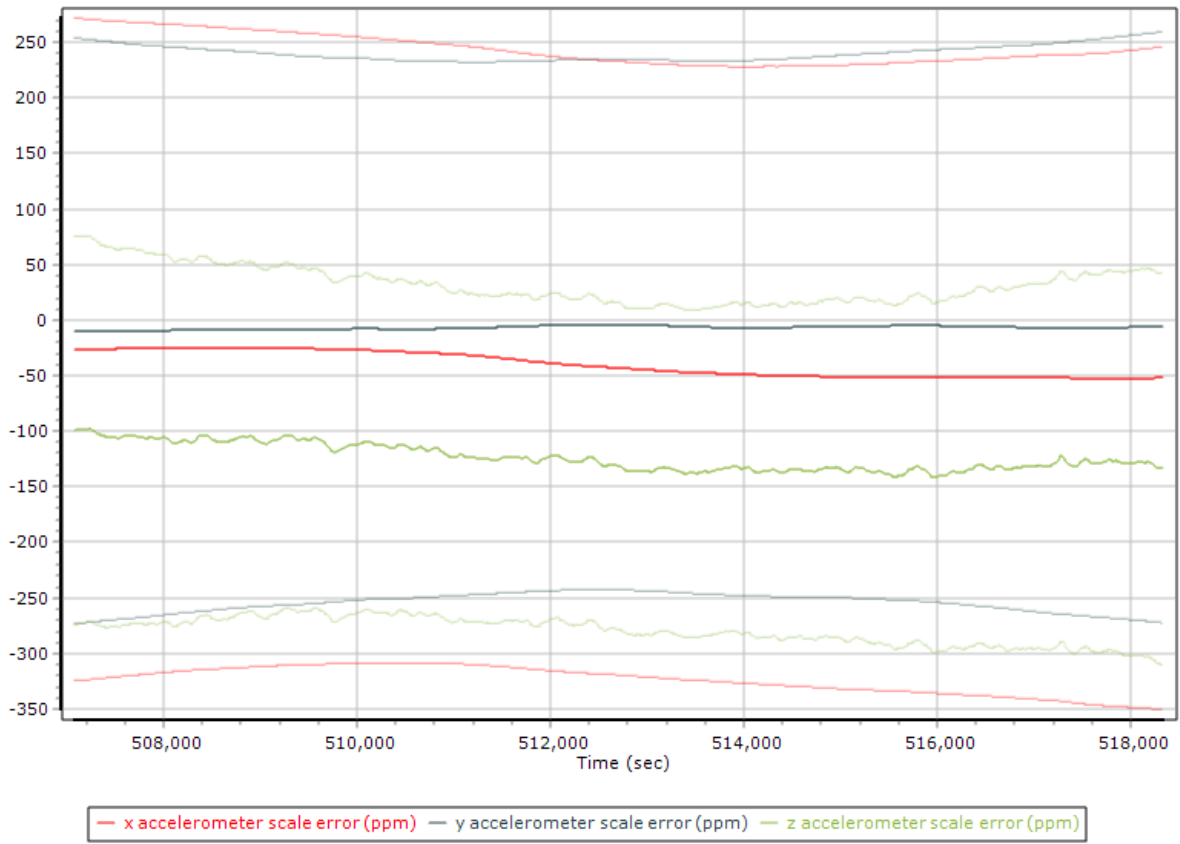
Start after launch Wait Time: 4.000 sec

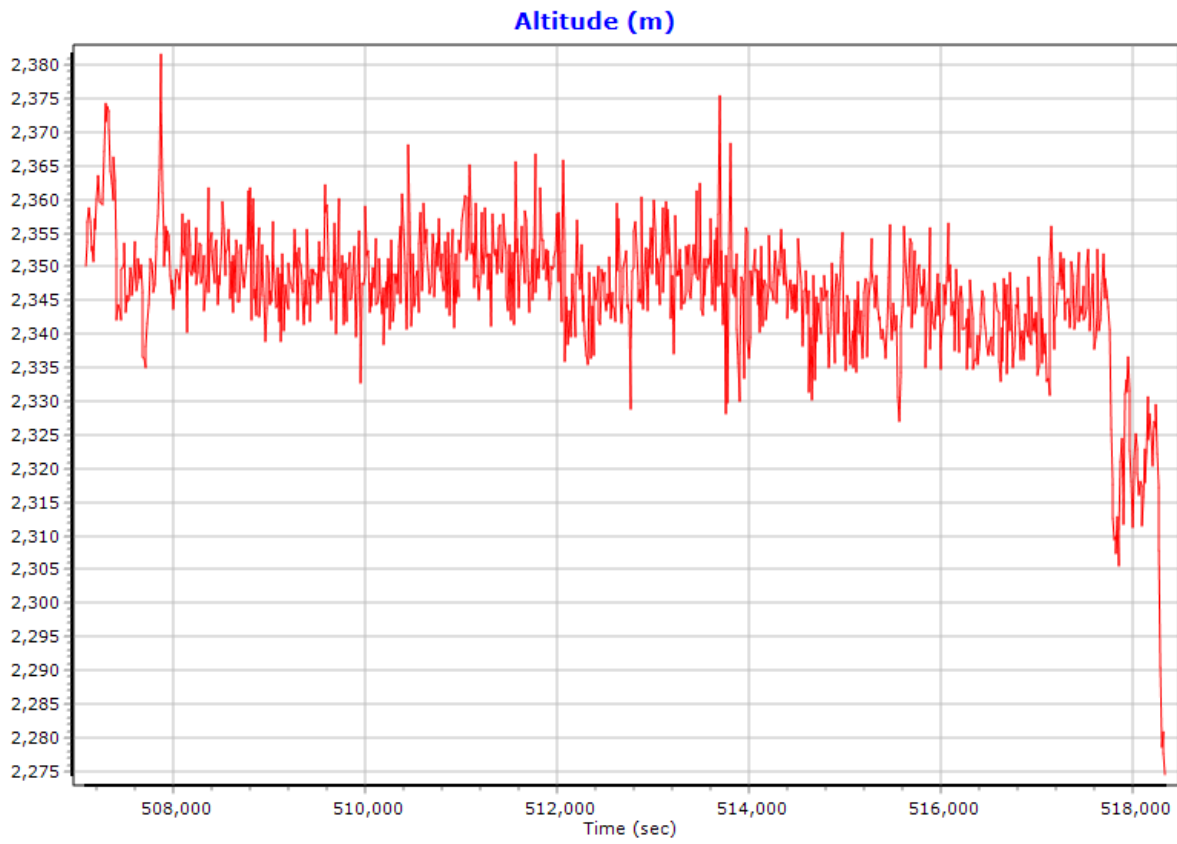
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	483972.000	501046.000	17074.000	End of file

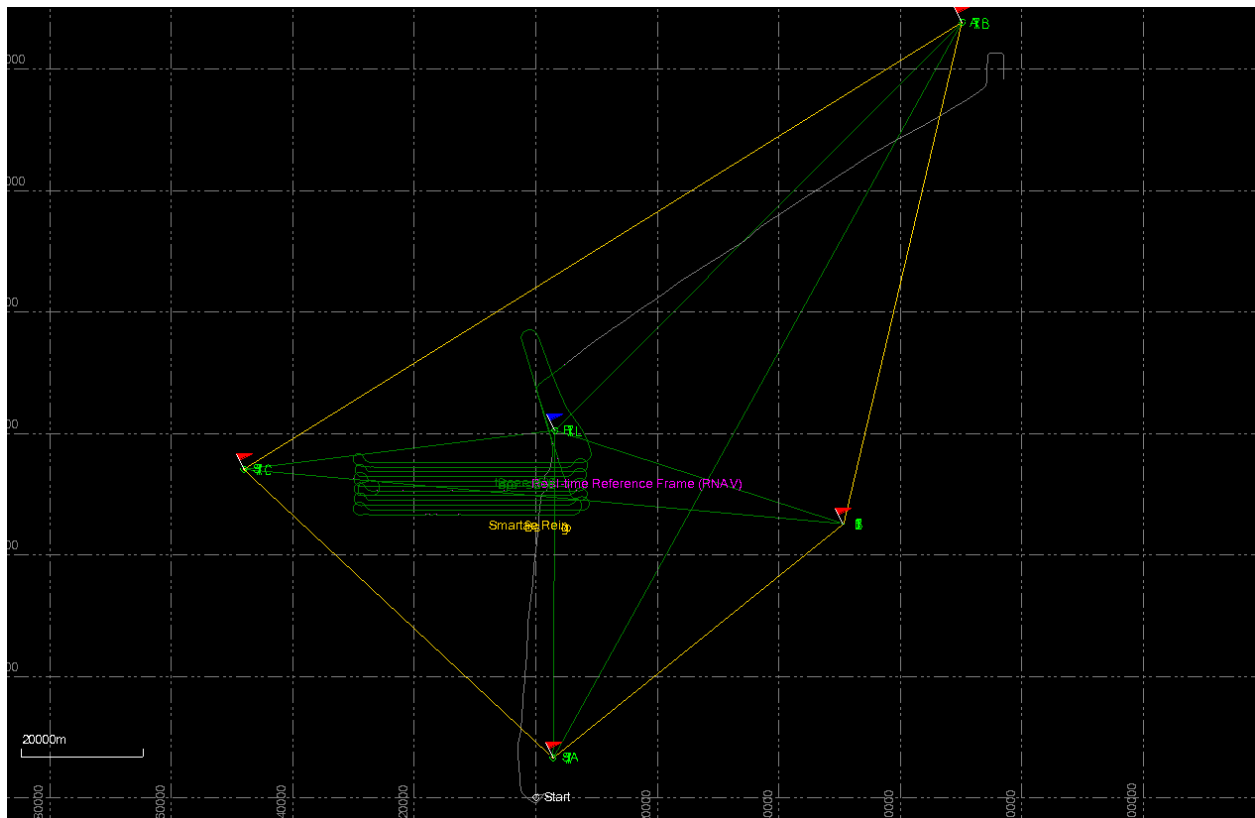
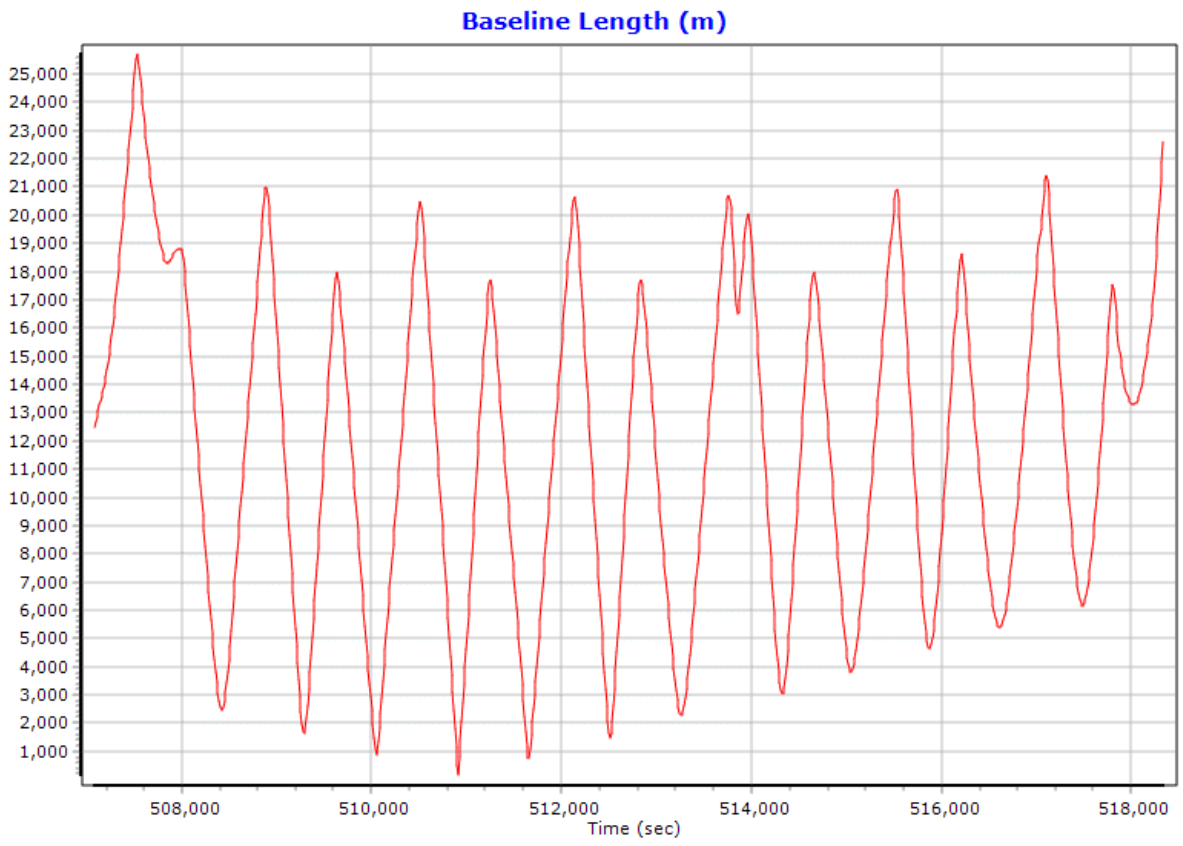
OK Cancel

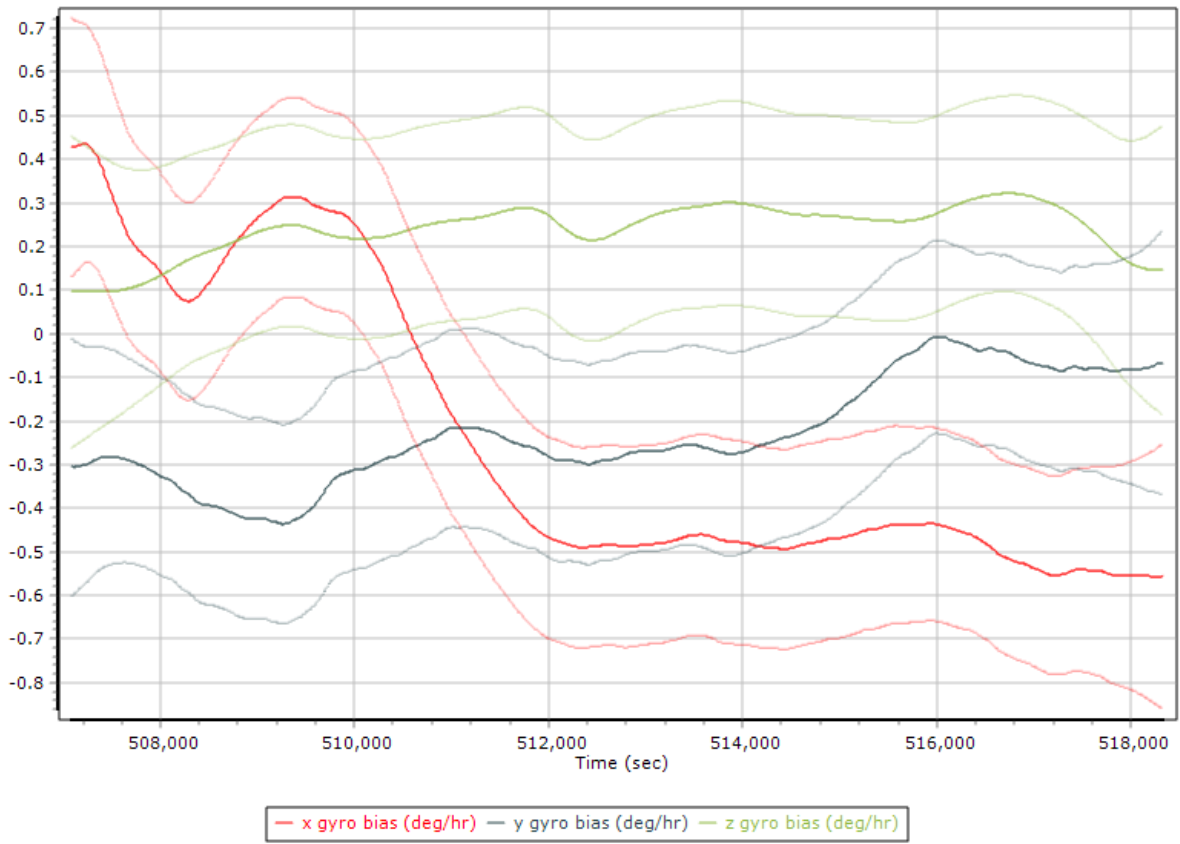
CAU18068B

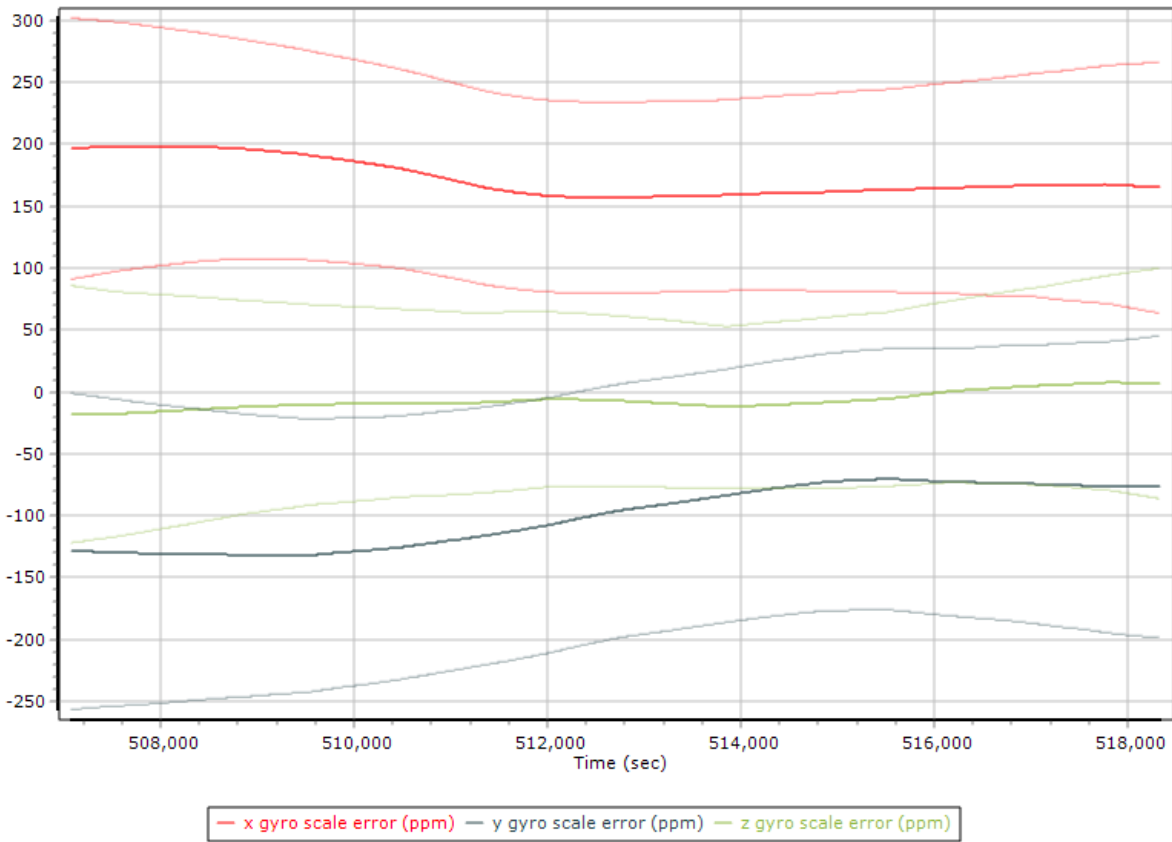












Project Settings [X]

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation: (Selected)

<3cm 10cm 50cm 1m 10m

Aircraft to Reference Mounting Angles

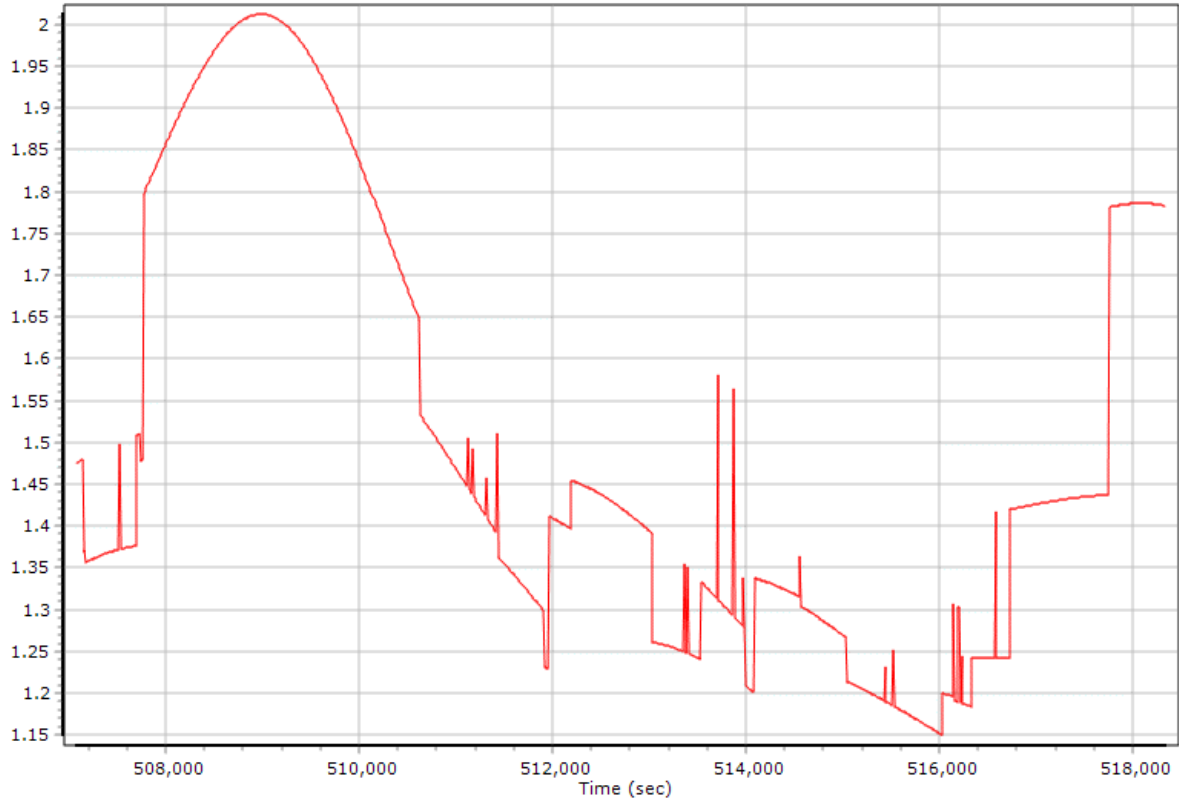
X:

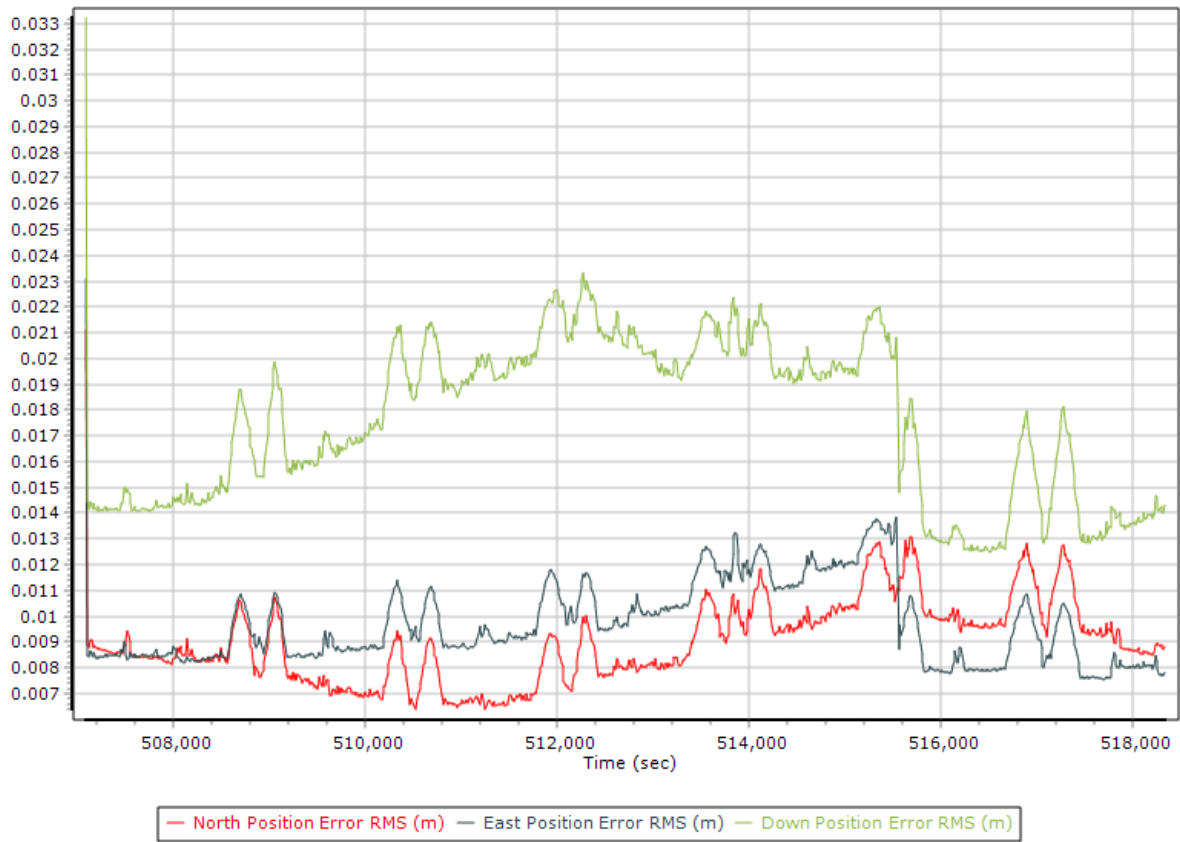
Y:

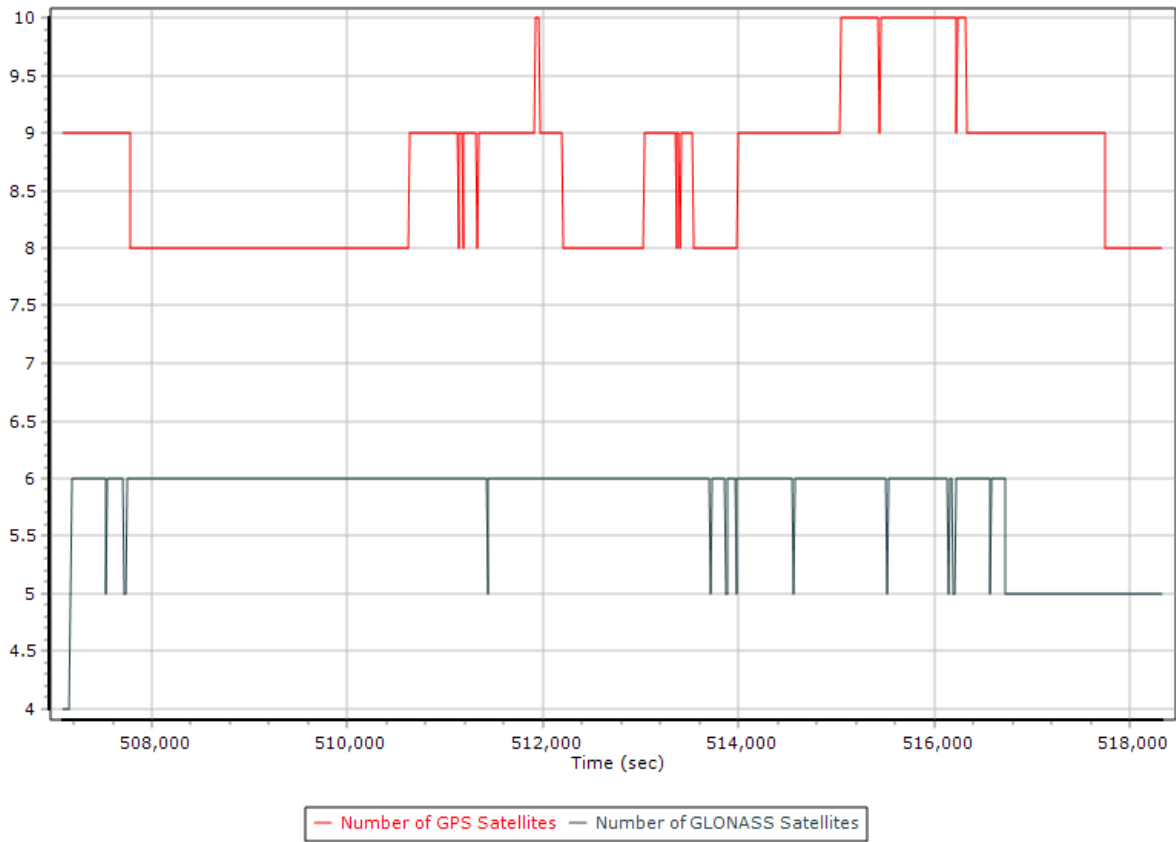
Z:

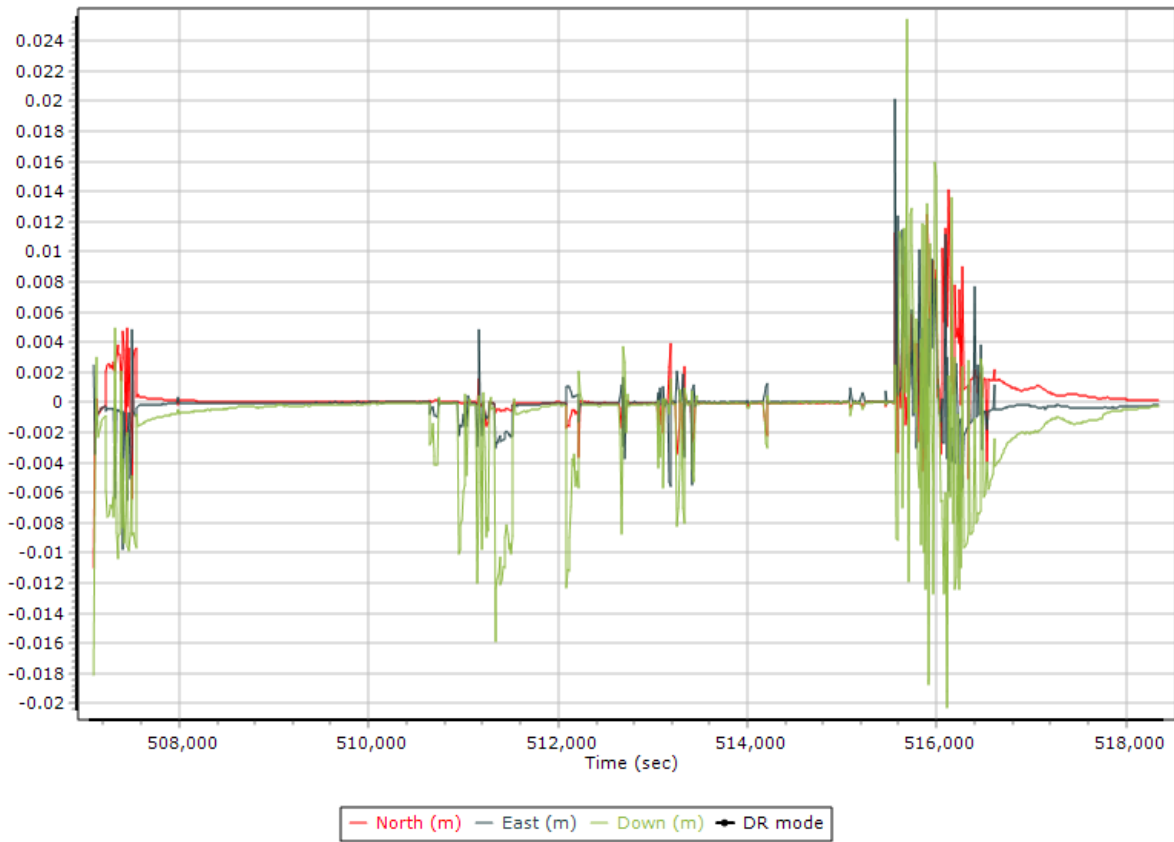
OK Cancel

PDOP









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: 505111.000
 End: 520015.000

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

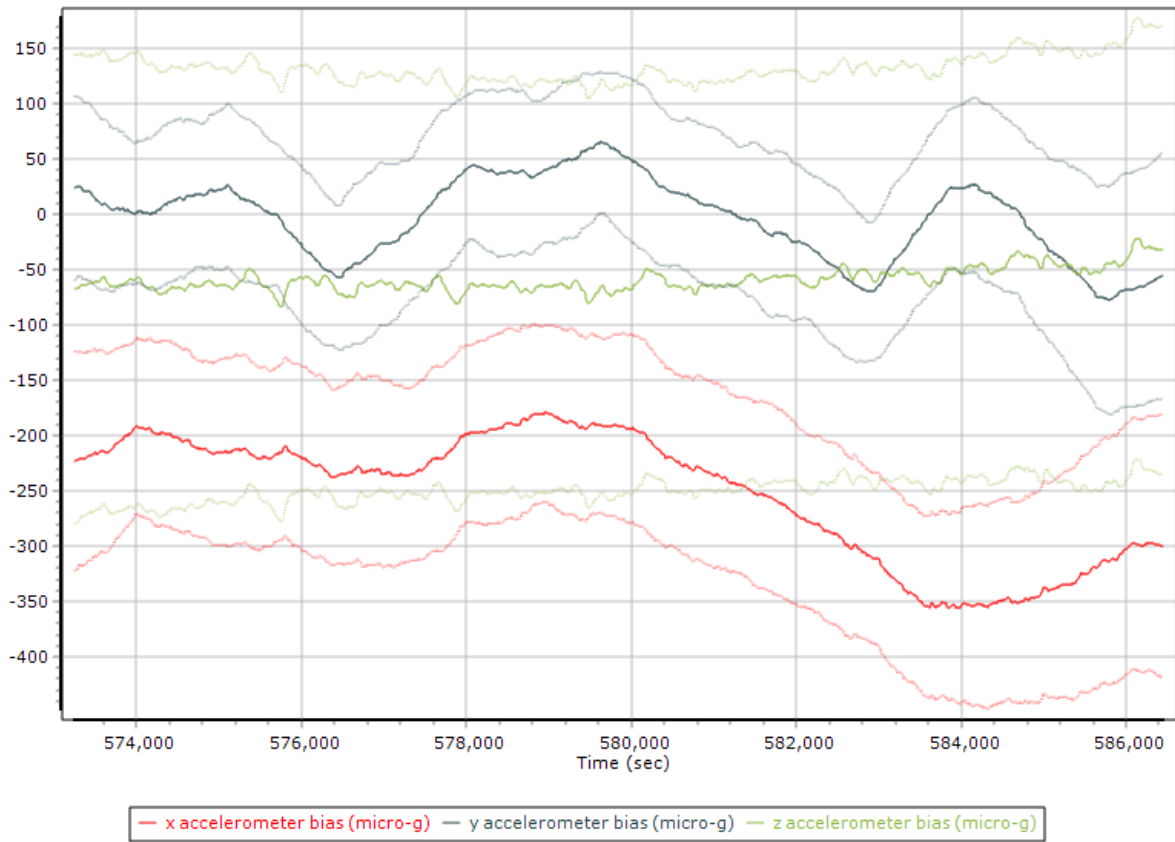
Processable Time Windows

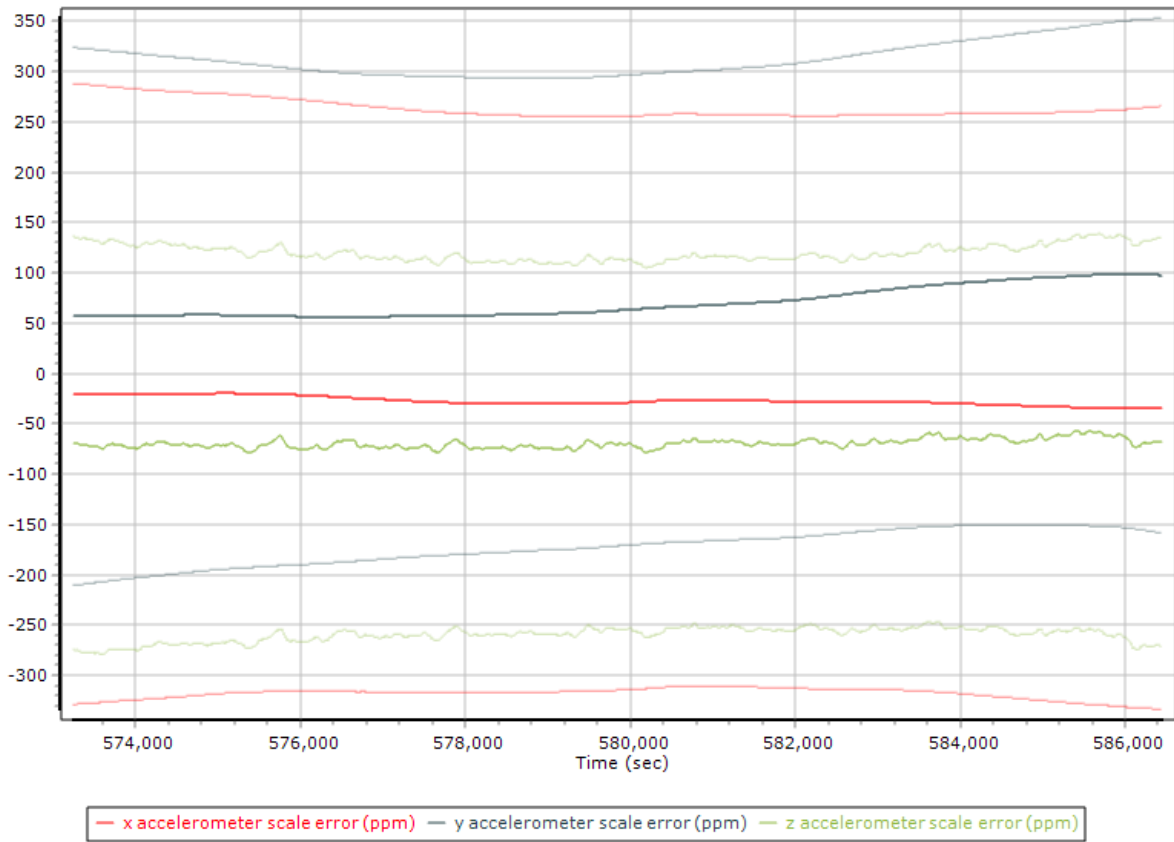
Start after launch Wait Time: 4.000 sec

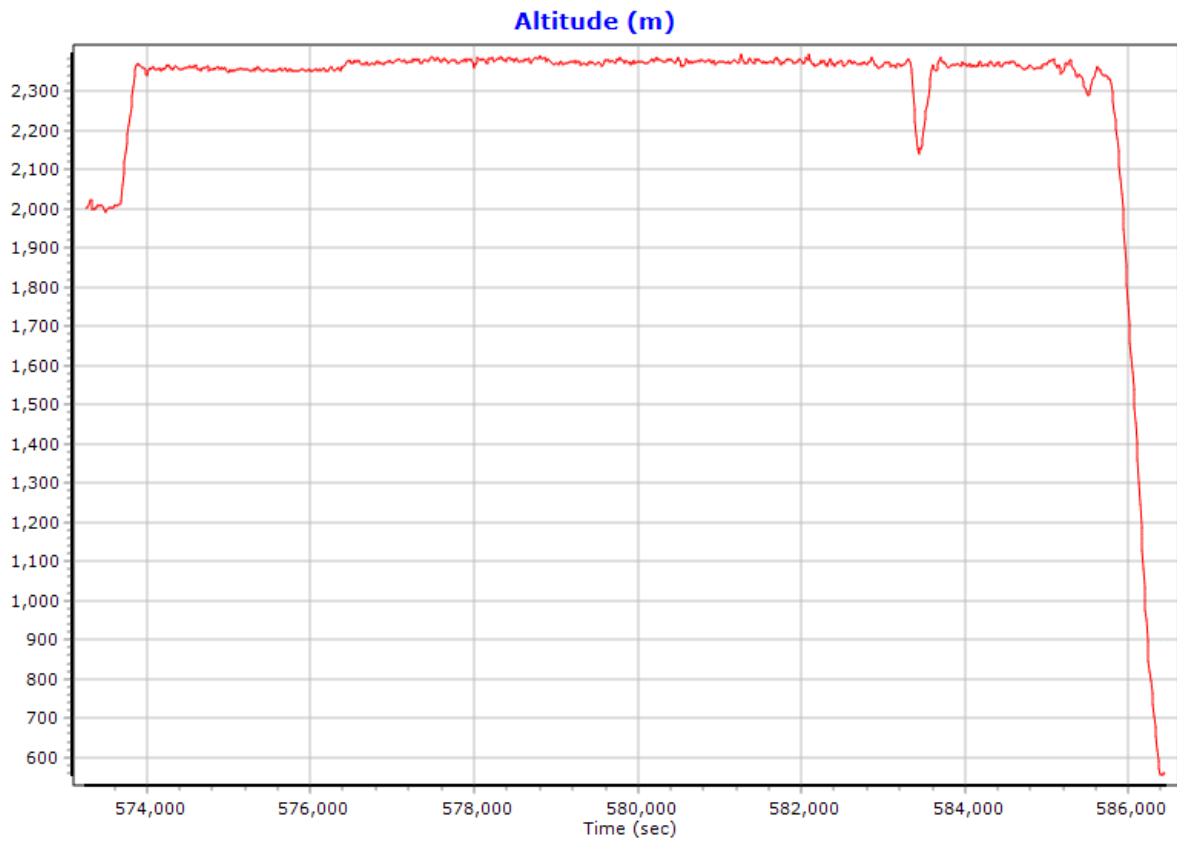
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	505111.000	520015.000	14904.000	End of file

OK Cancel

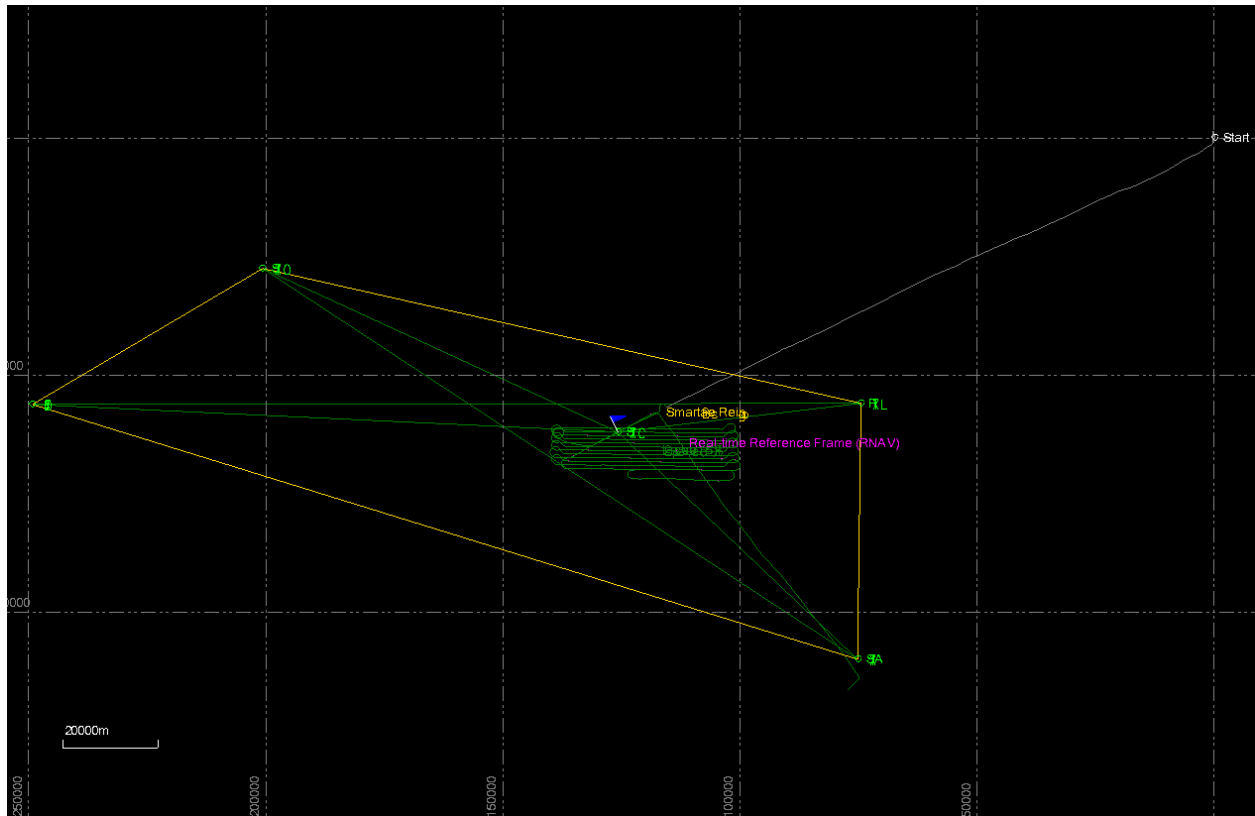
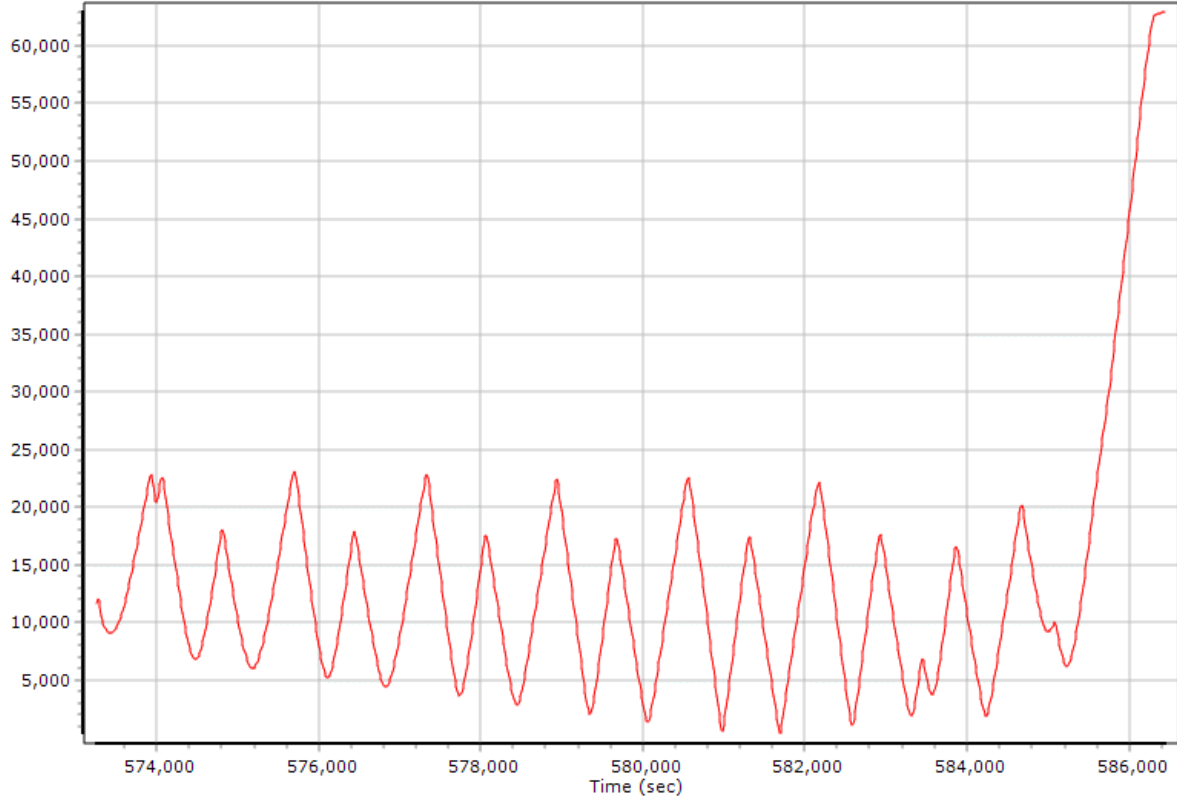
CAU18069A

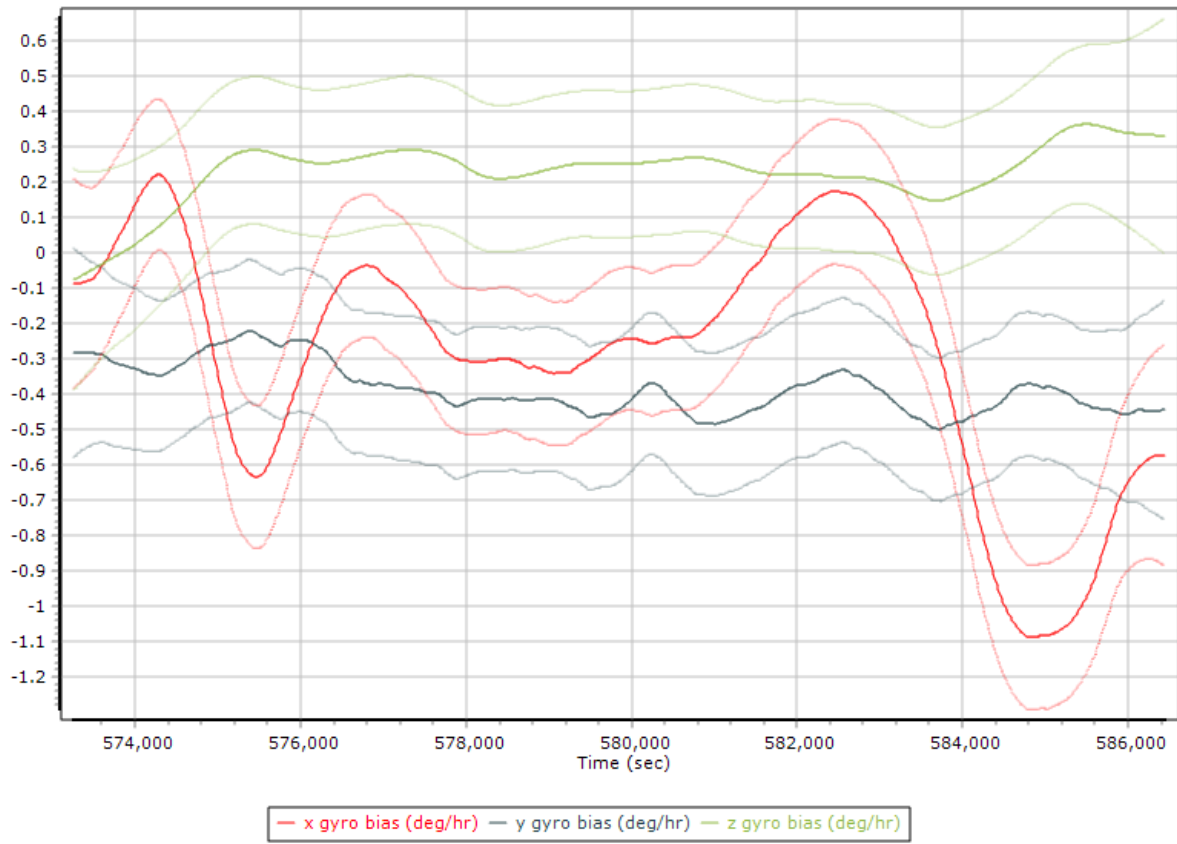


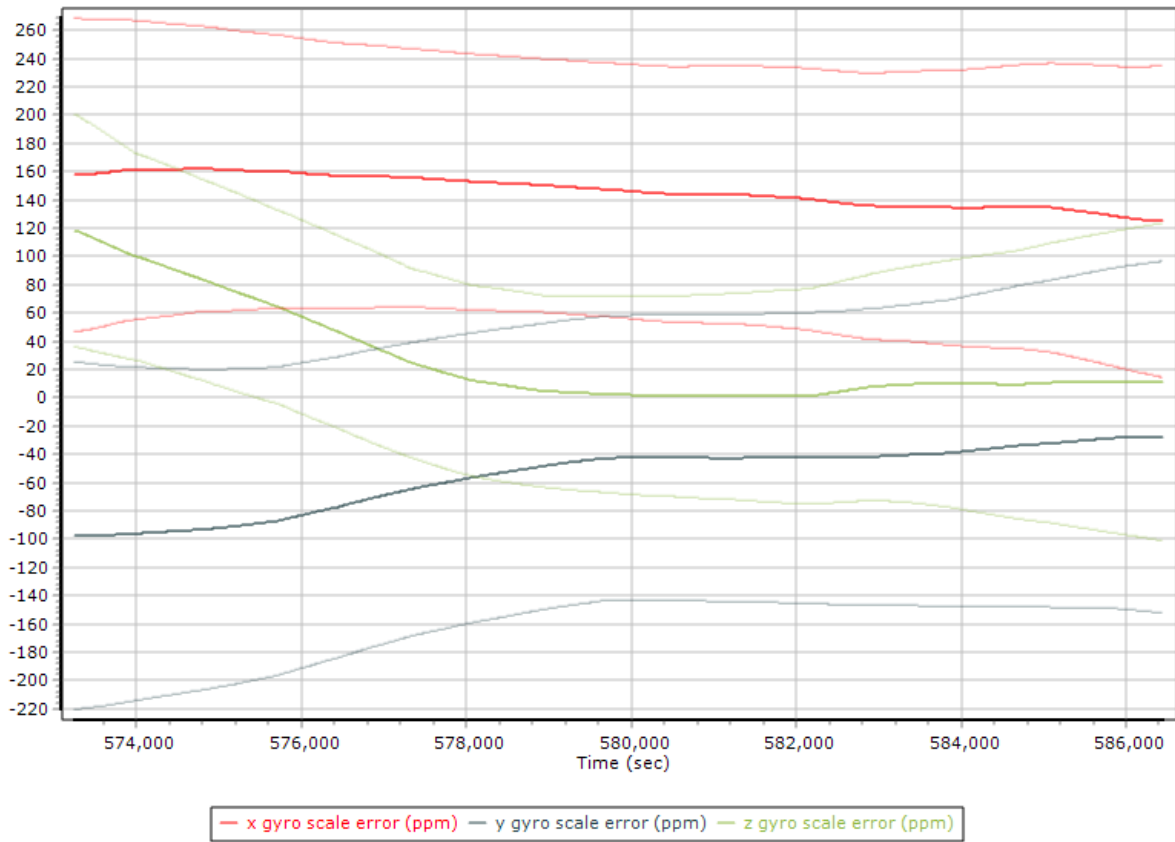




Baseline Length (m)







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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

Aircraft to Reference Mounting Angles

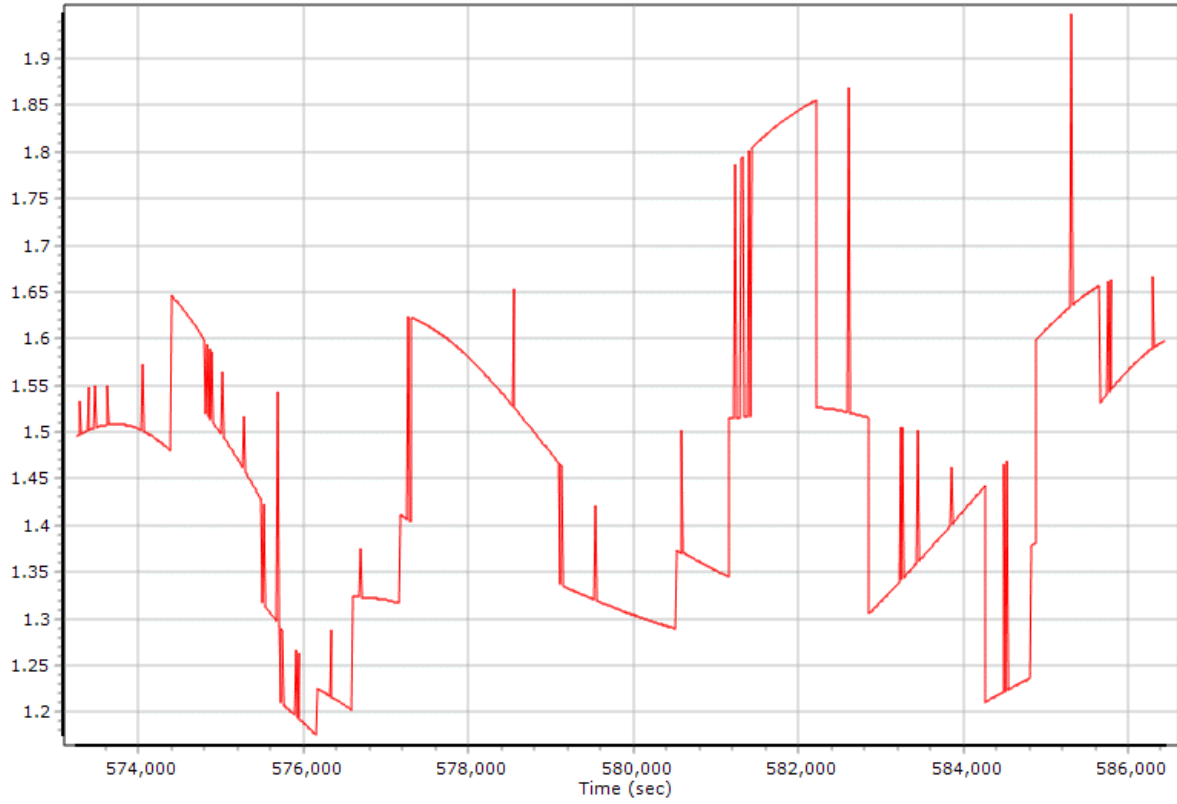
X:

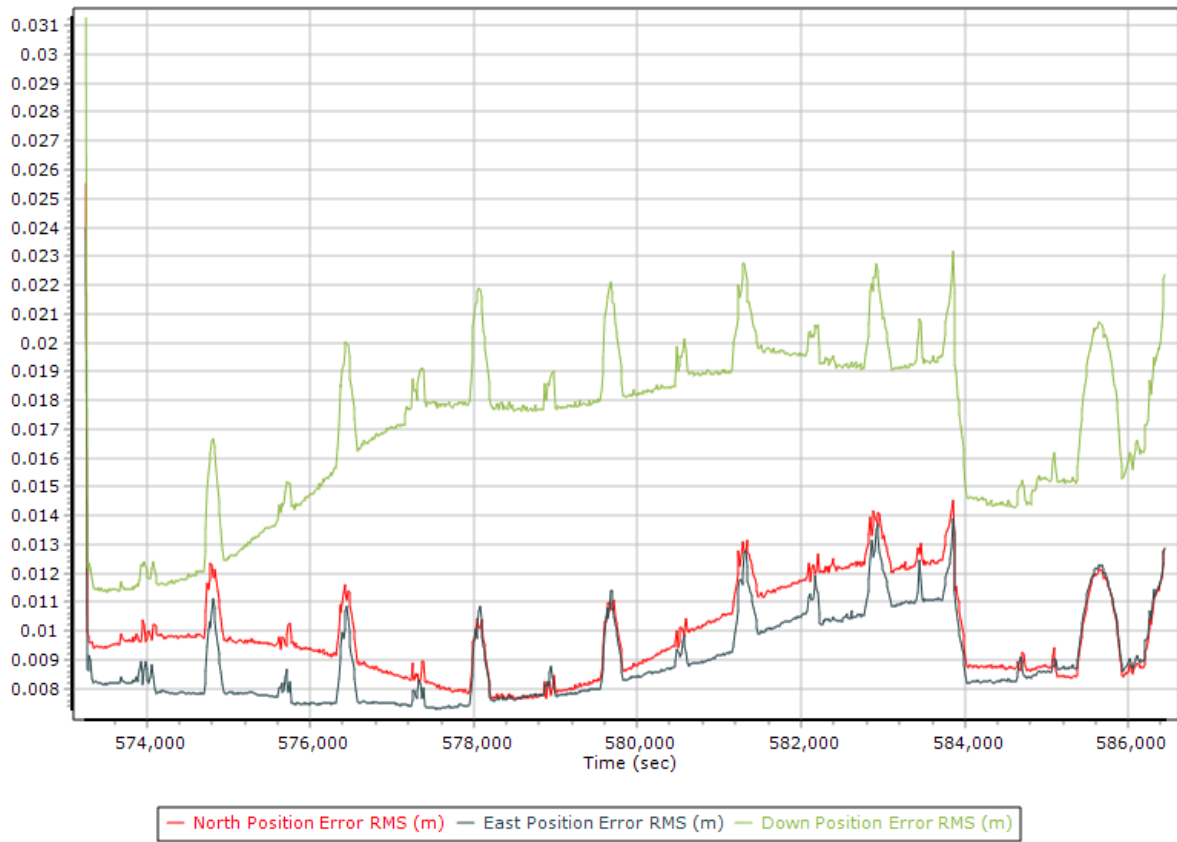
Y:

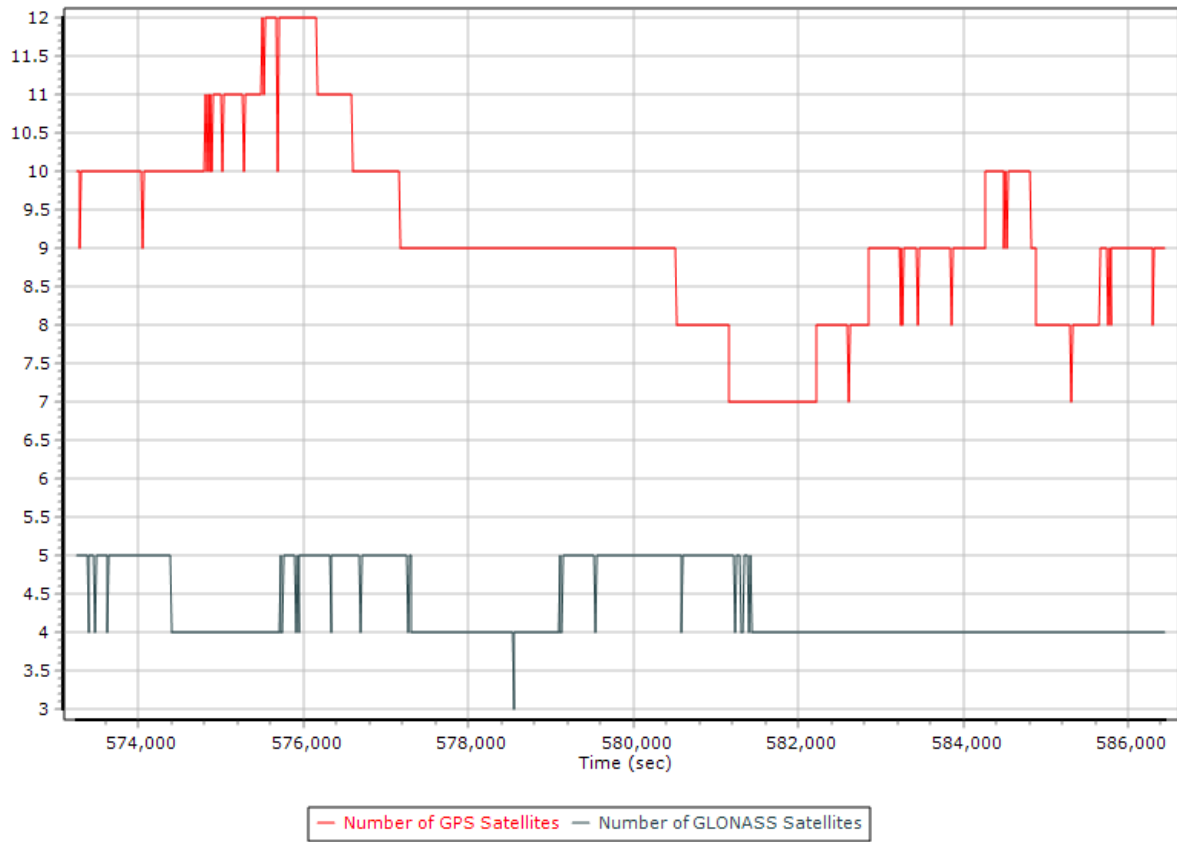
Z:

OK Cancel

PDOP









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: 569403.000
 End: 586465.000

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

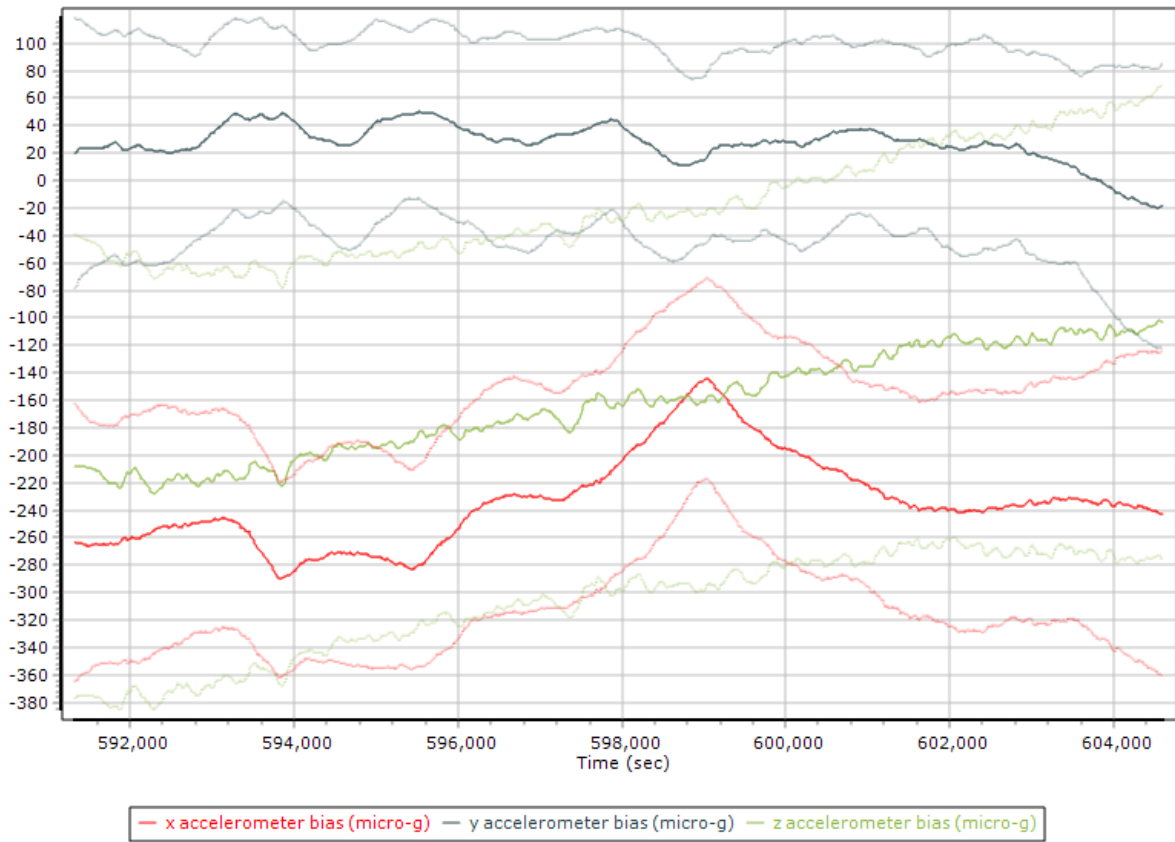
Processable Time Windows

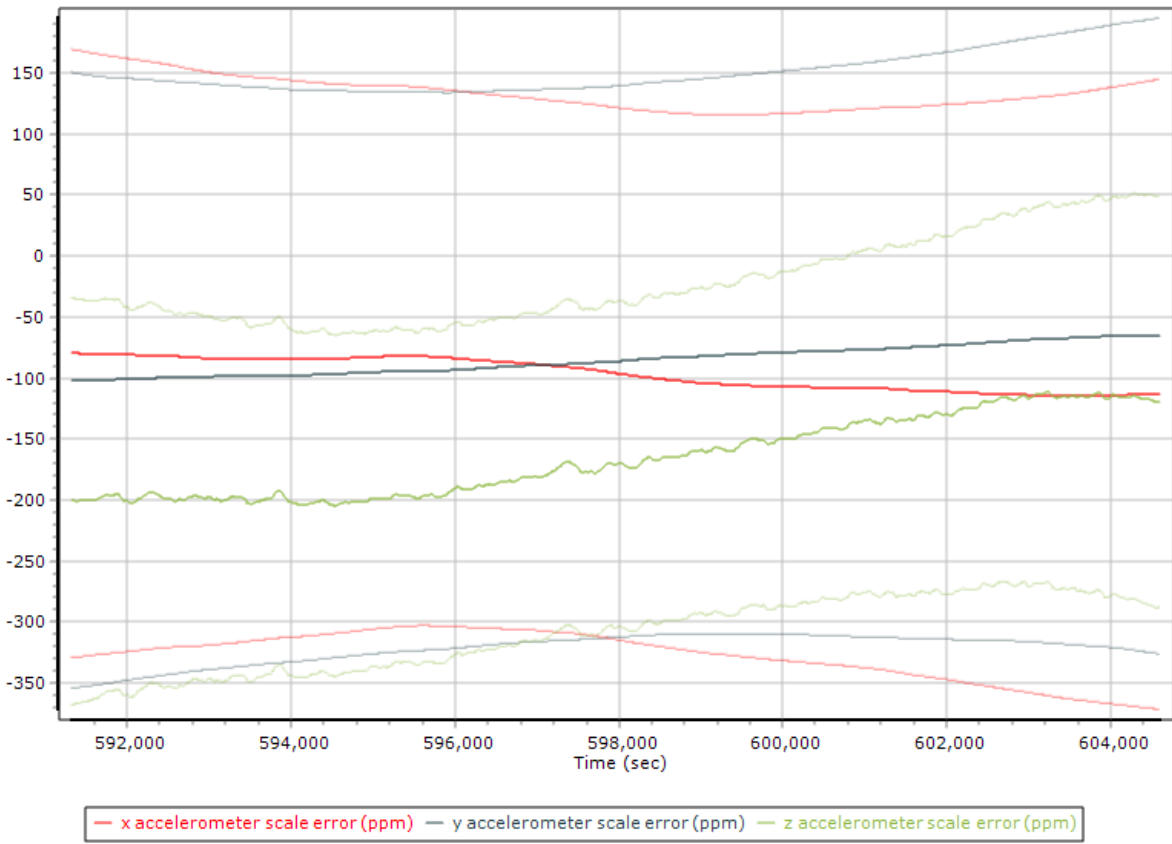
Start after launch Wait Time: 4.000 sec

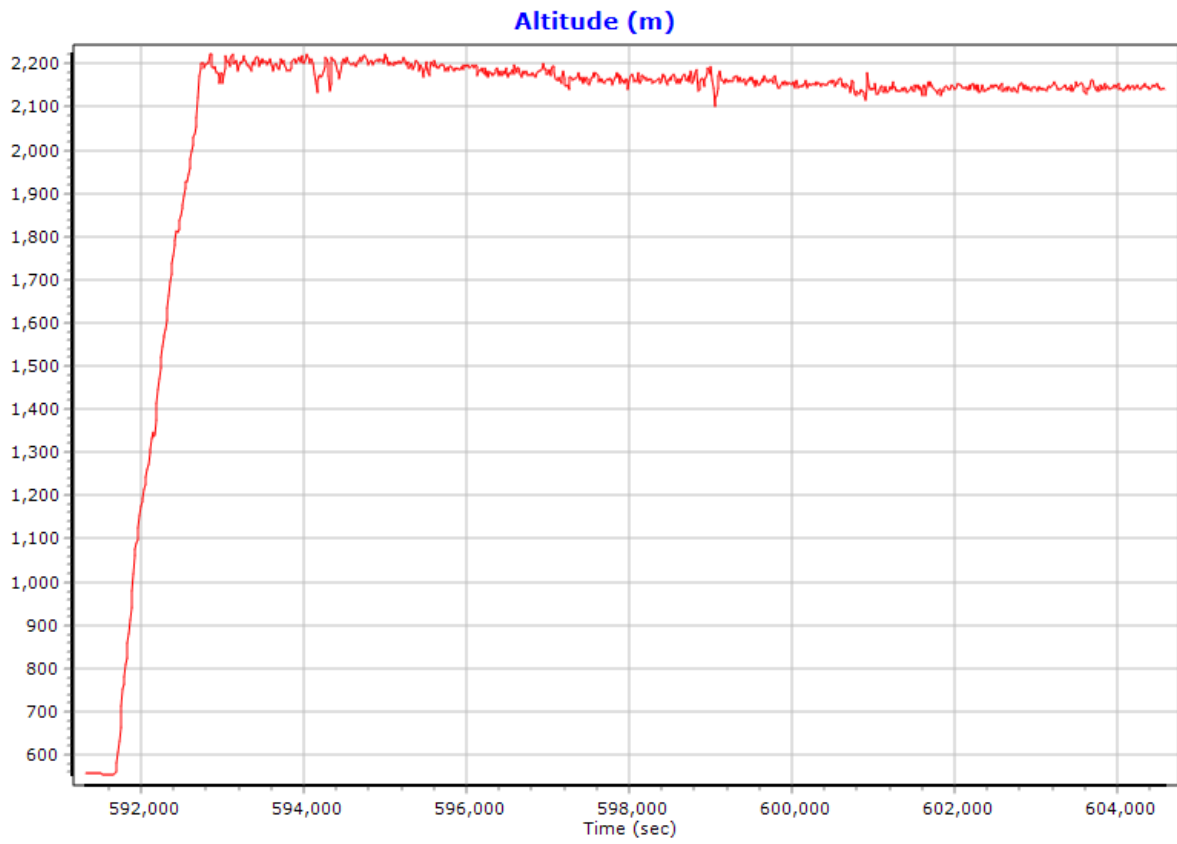
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	569403.000	586465.000	17062.000	End of file

OK Cancel

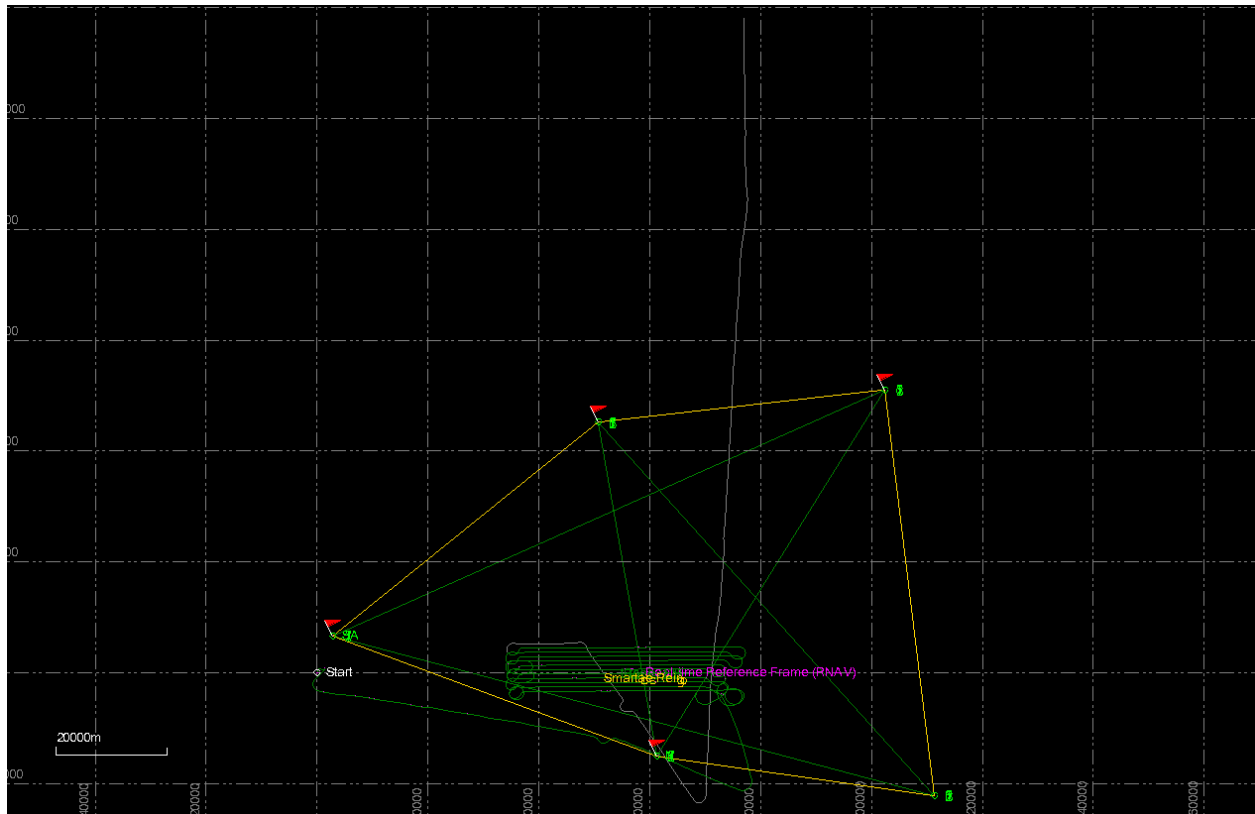
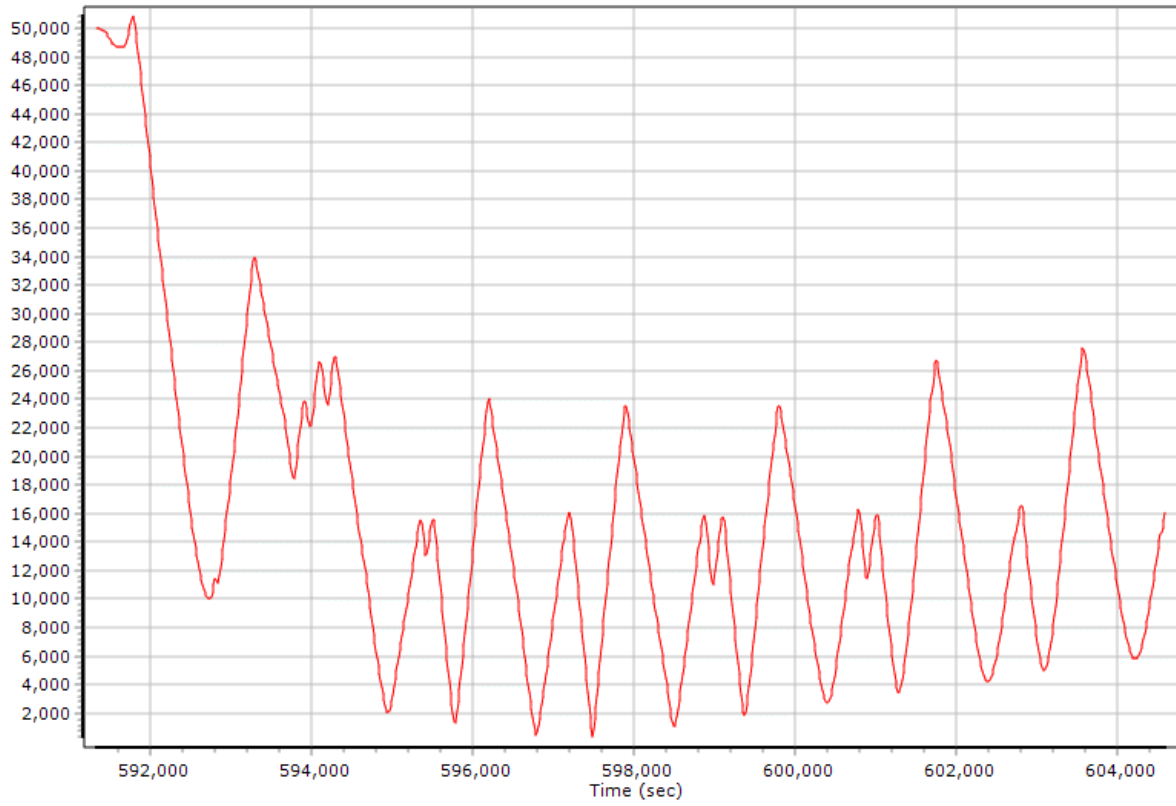
CAU18069B

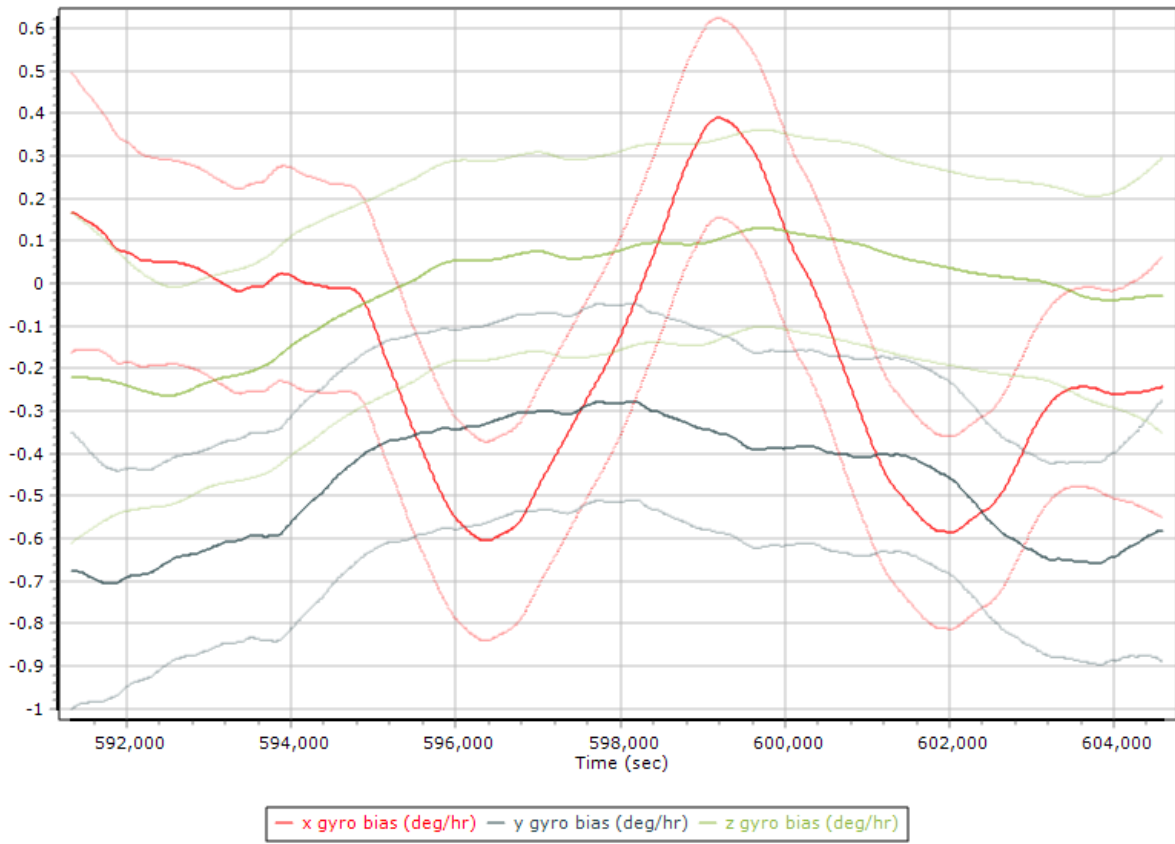


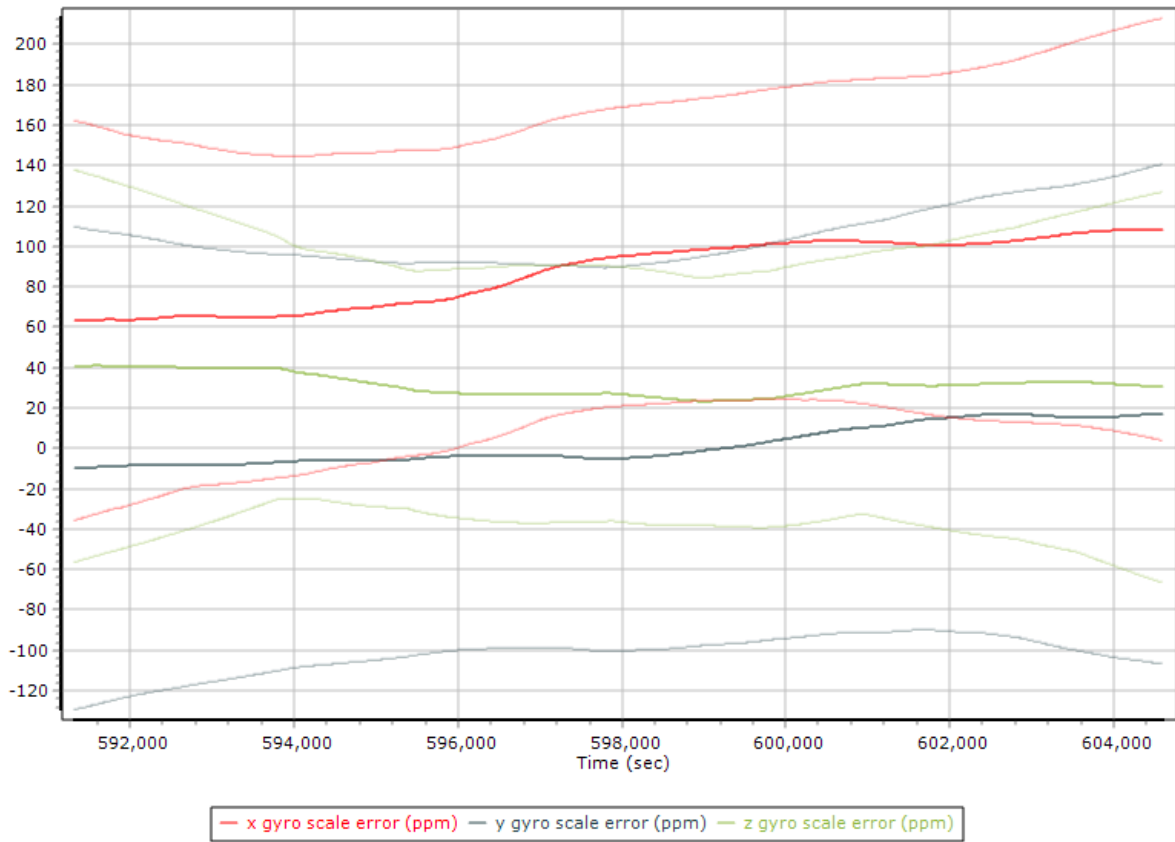




Baseline Length (m)







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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

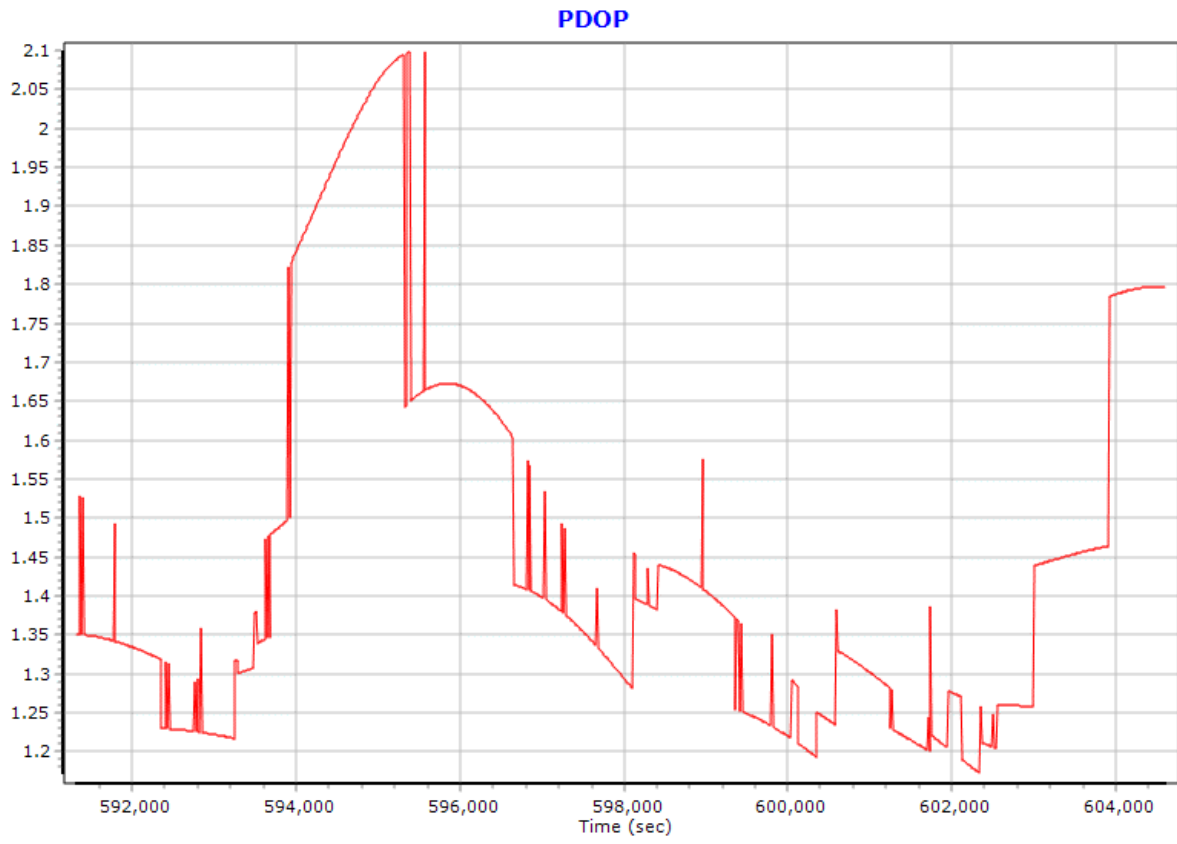
<3cm 10cm 50cm 1m 10m

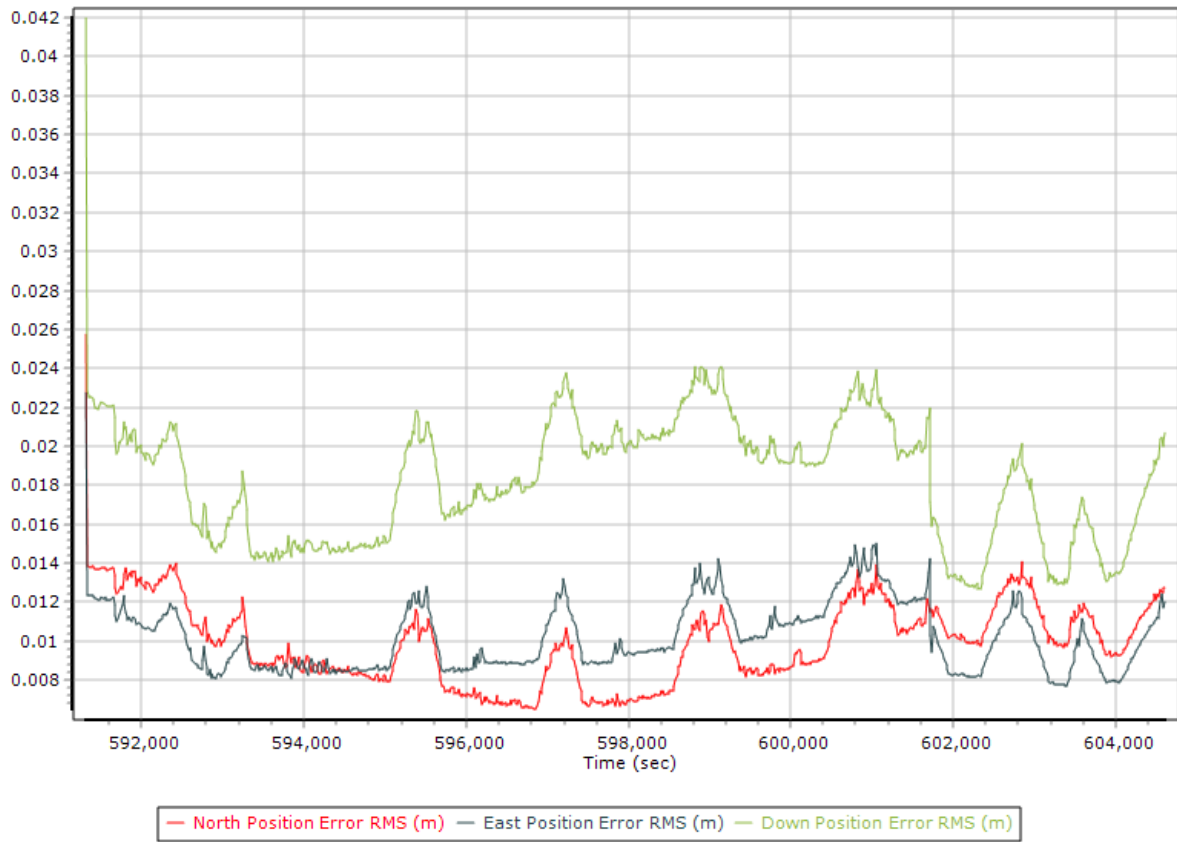
Aircraft to Reference Mounting Angles

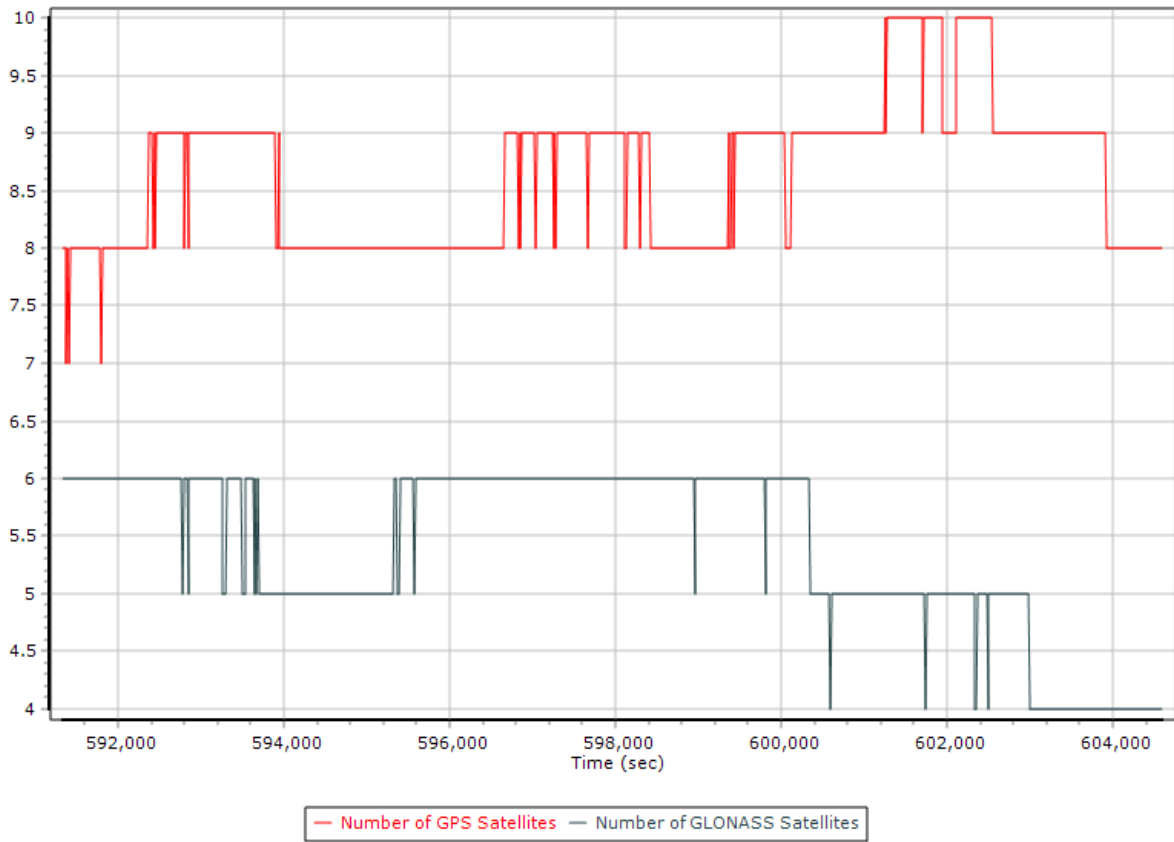
X:

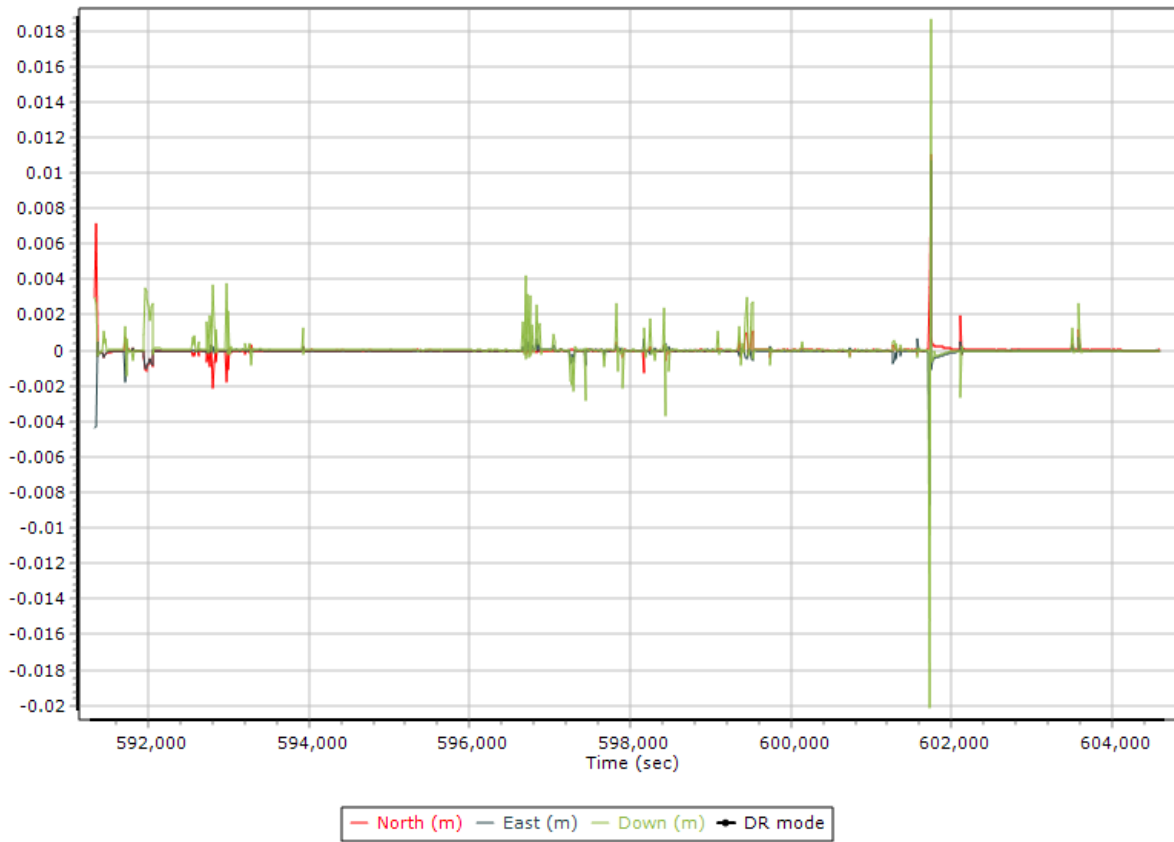
Y:

Z:









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: 590903.000
End: 608400.000

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

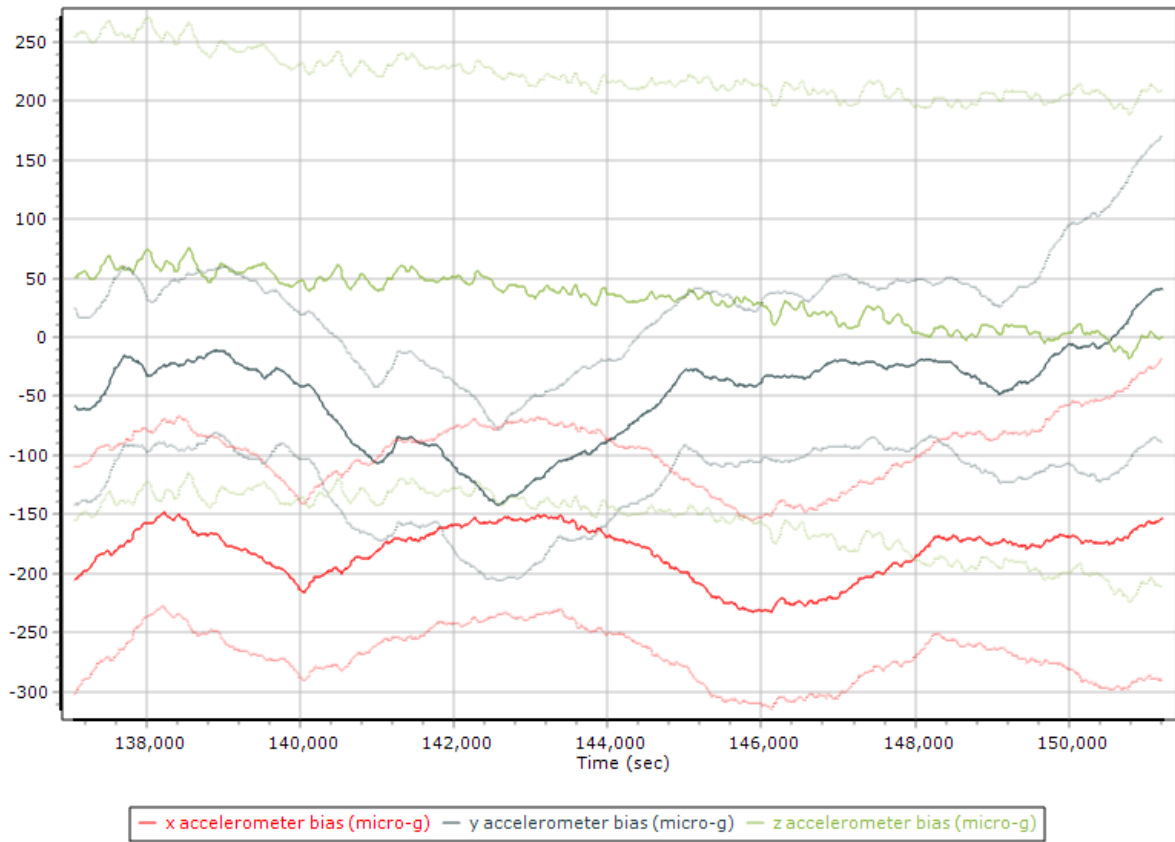
Processable Time Windows

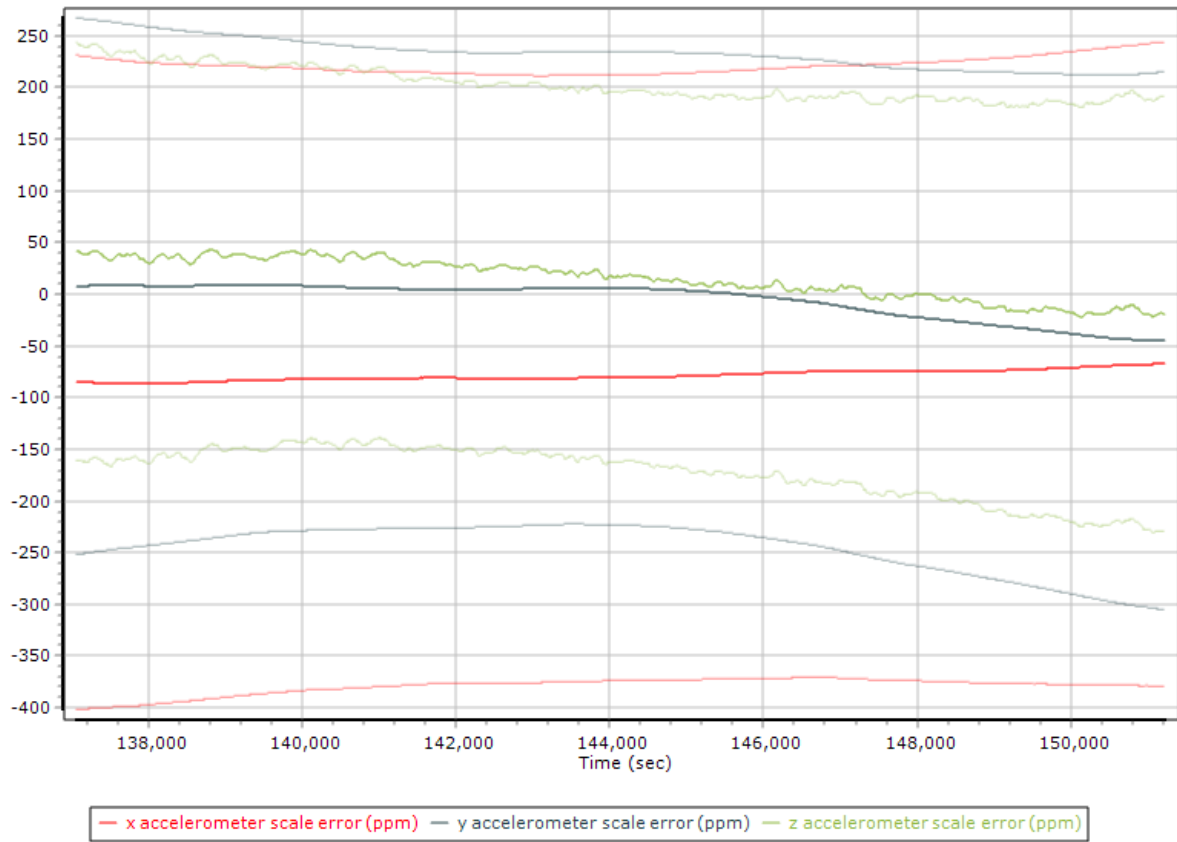
Start after launch Wait Time: 4.000 sec

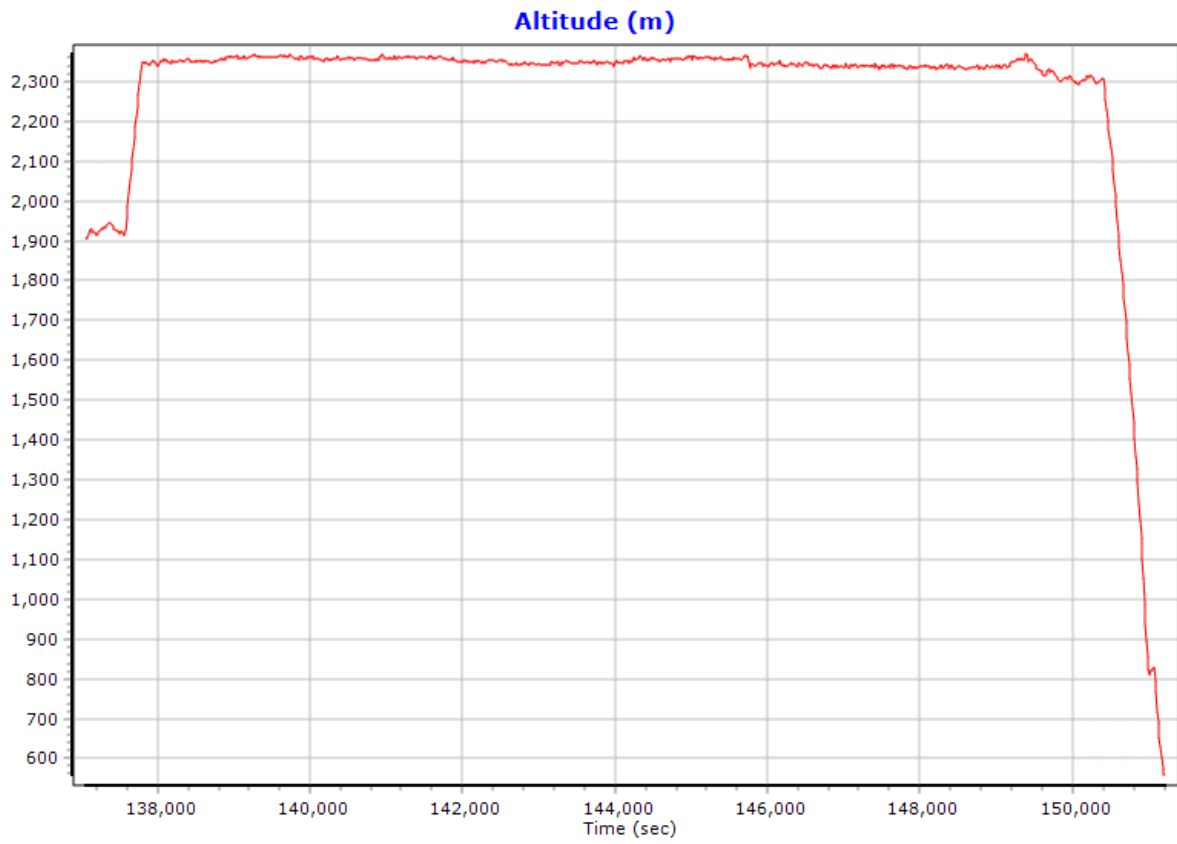
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	590903.000	608400.000	17497.000	End of file

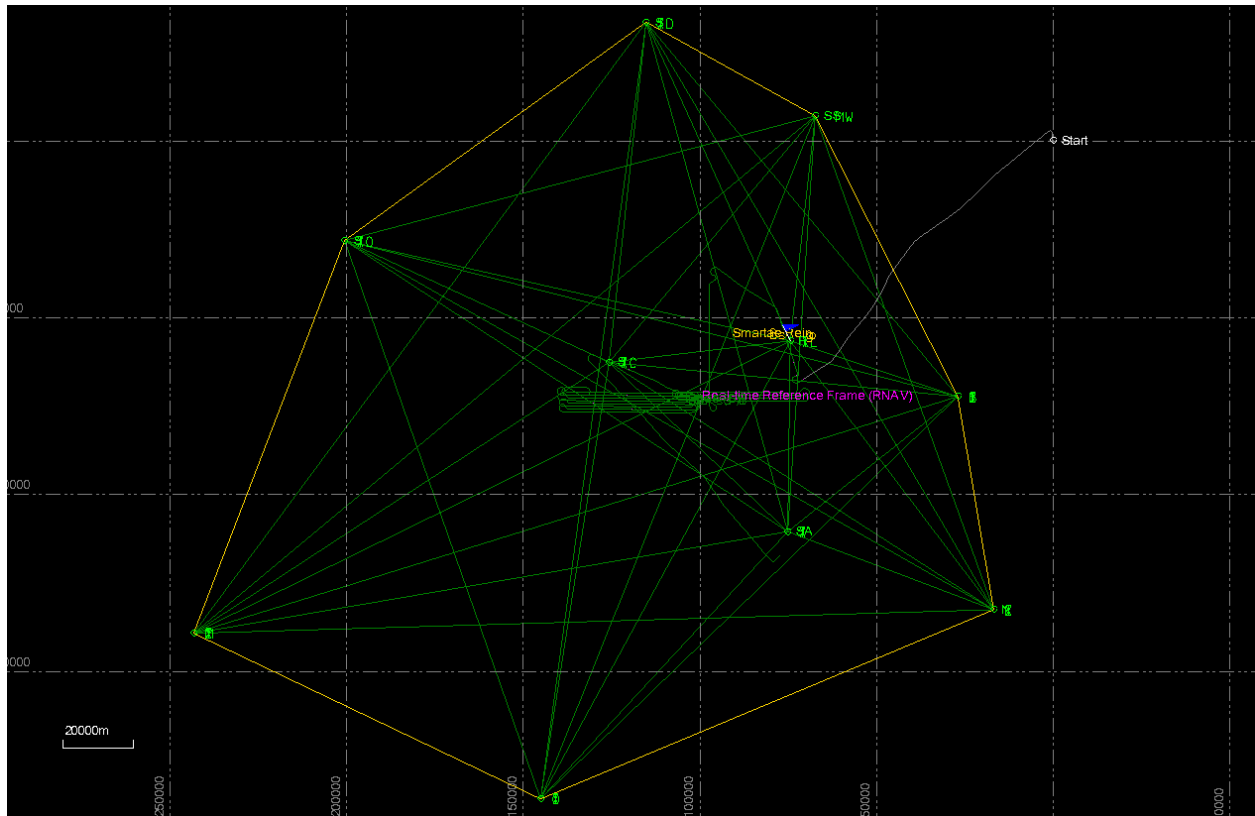
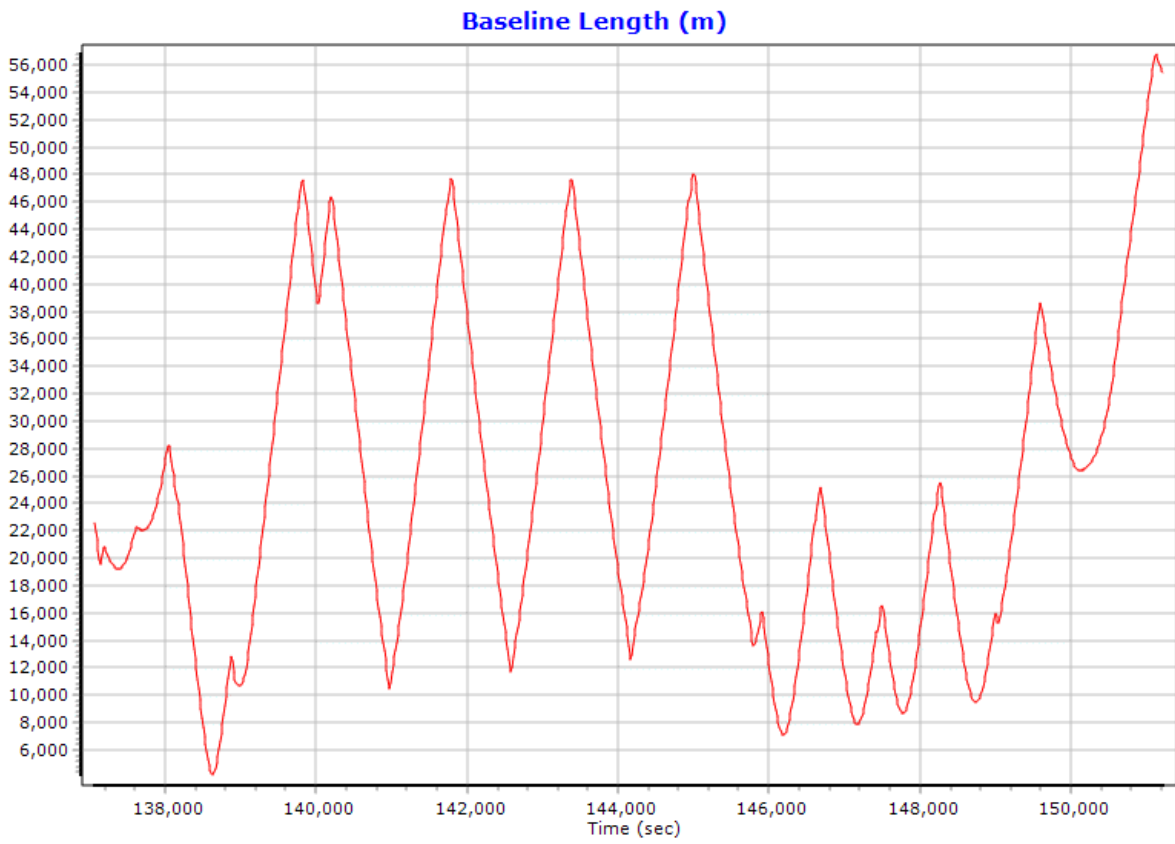
OK Cancel

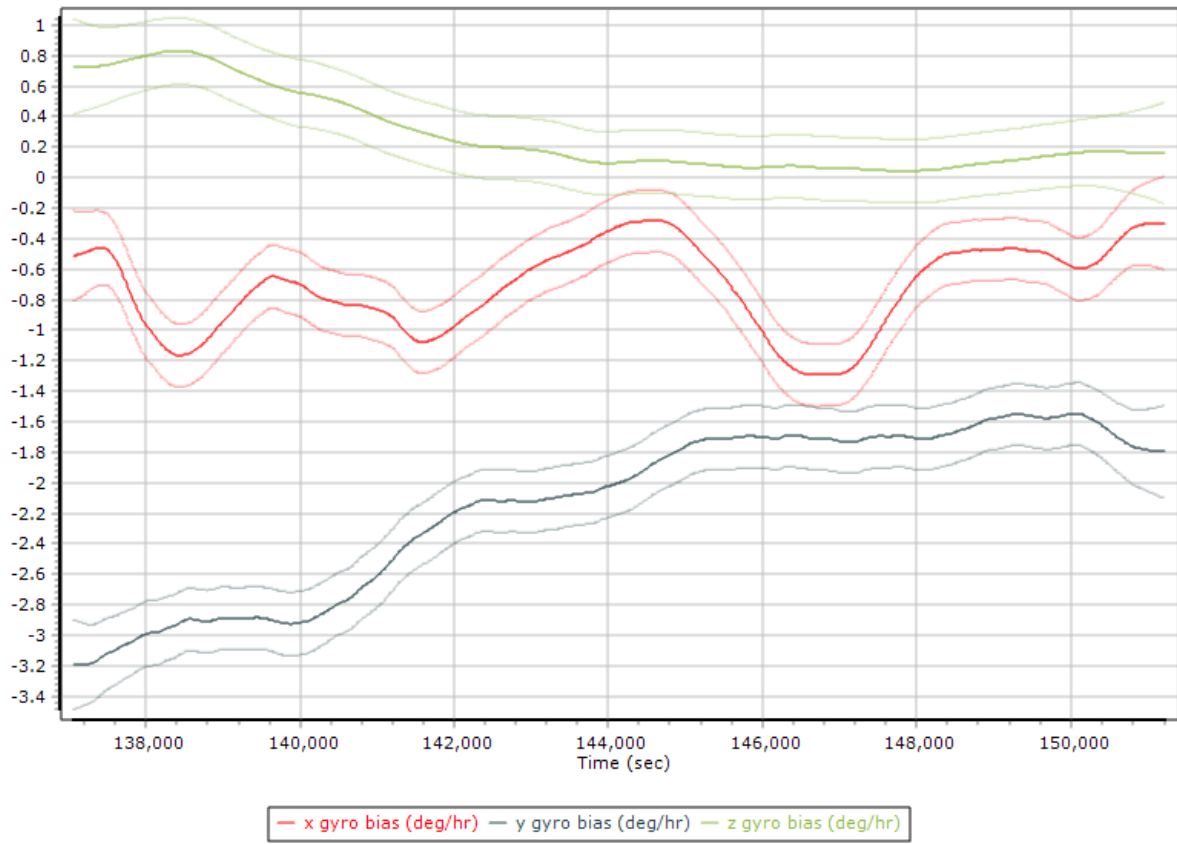
CAU18071A

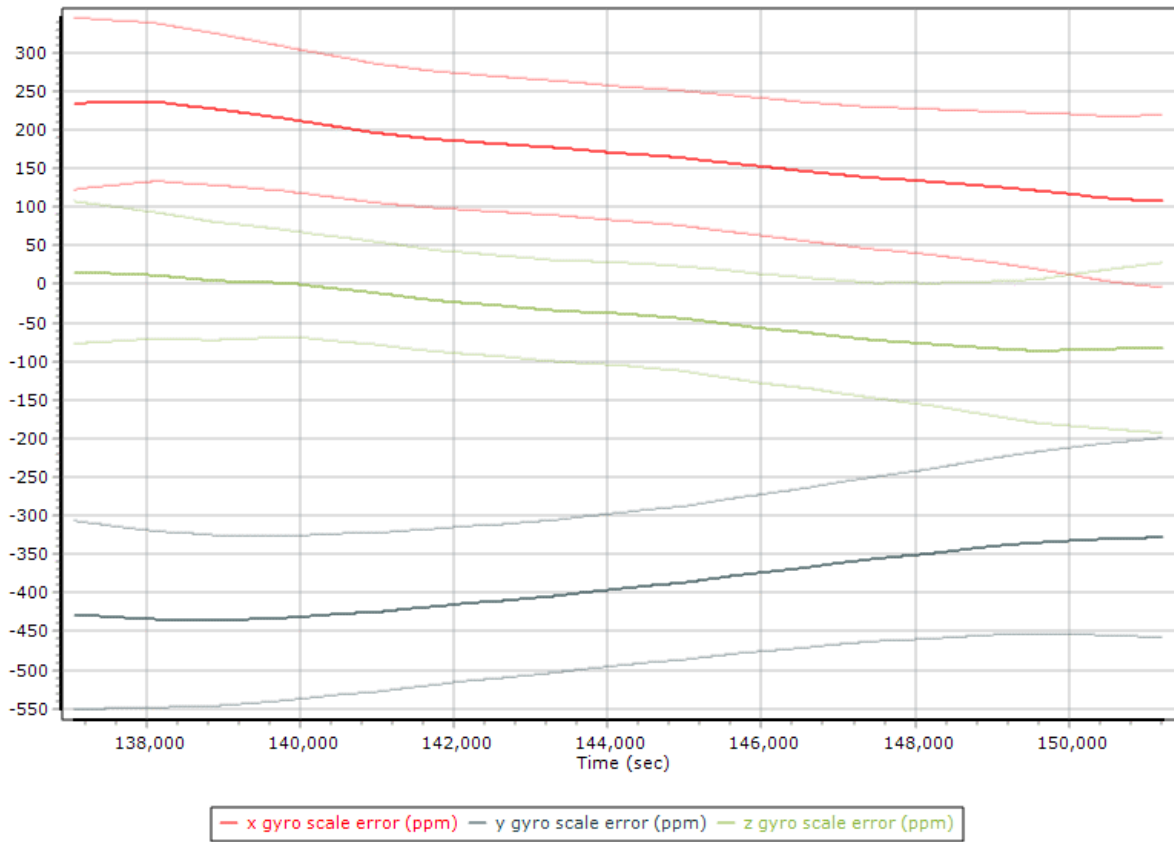












Project Settings [X]

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation: (Selected)

<3cm 10cm 50cm 1m 10m

Aircraft to Reference Mounting Angles

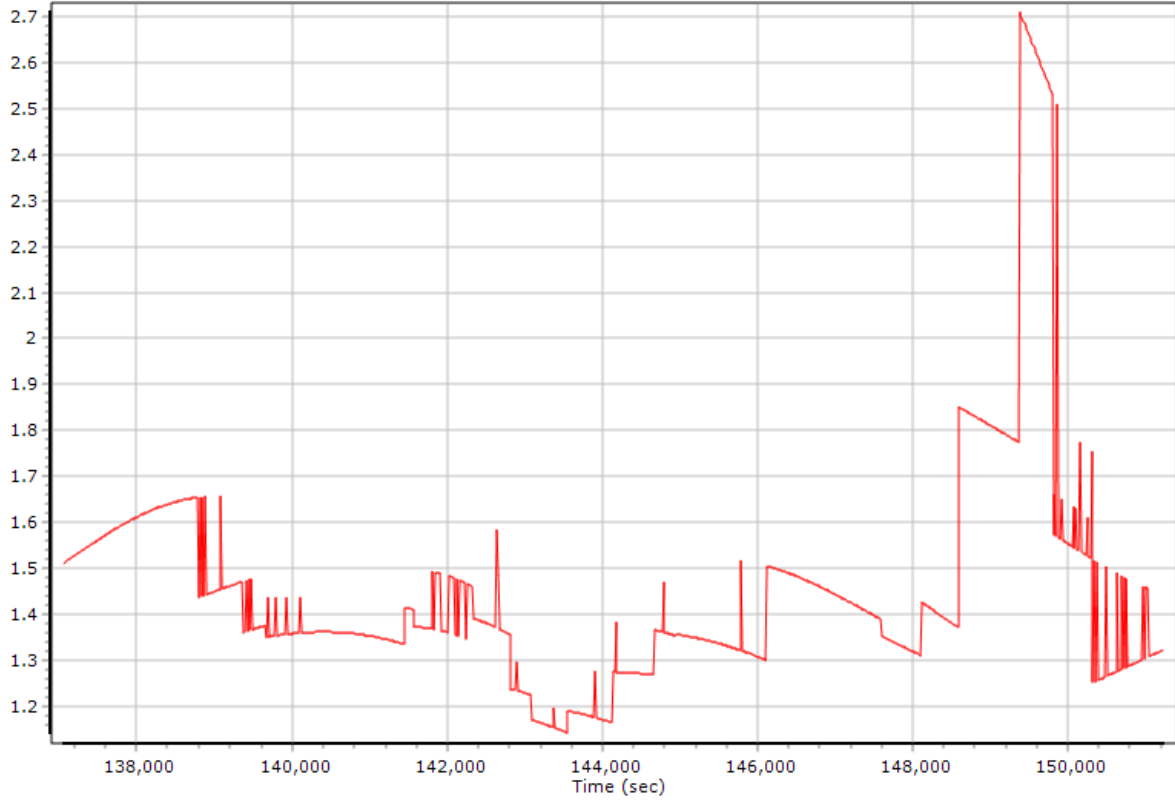
X:

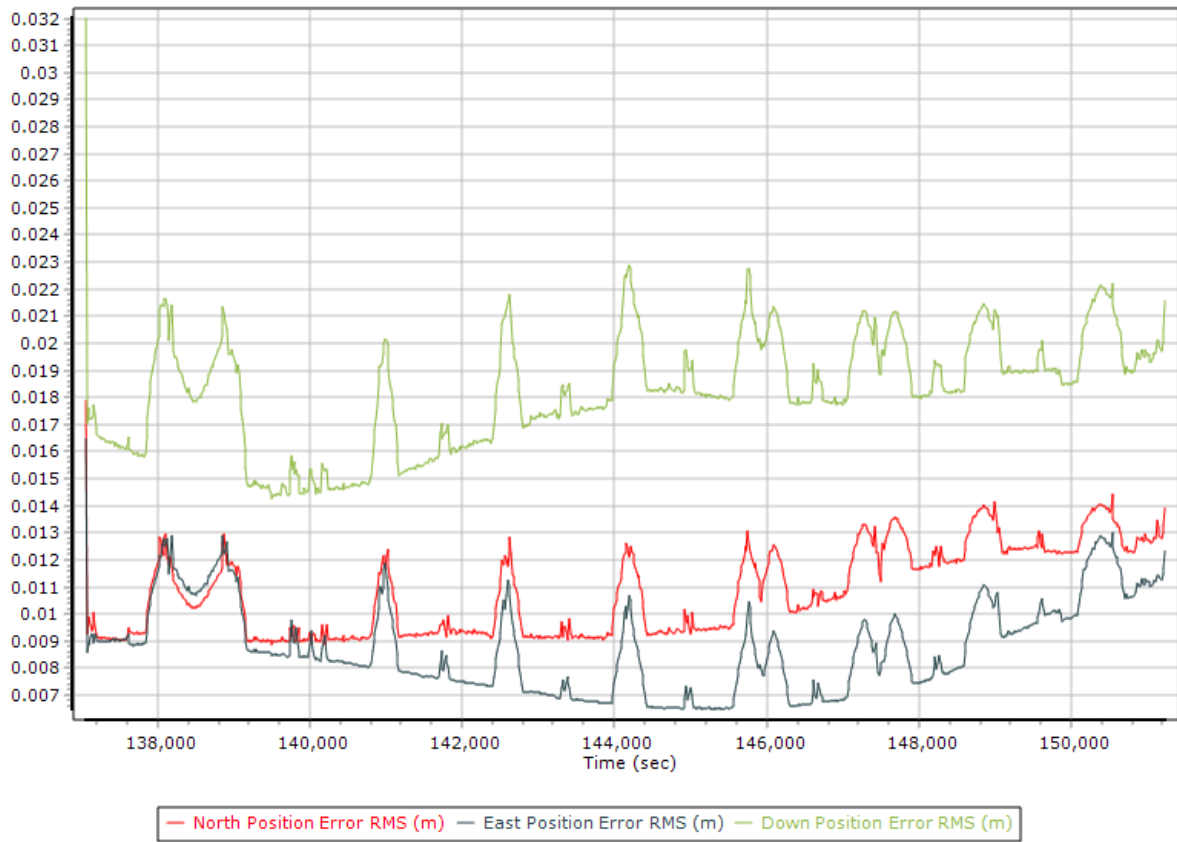
Y:

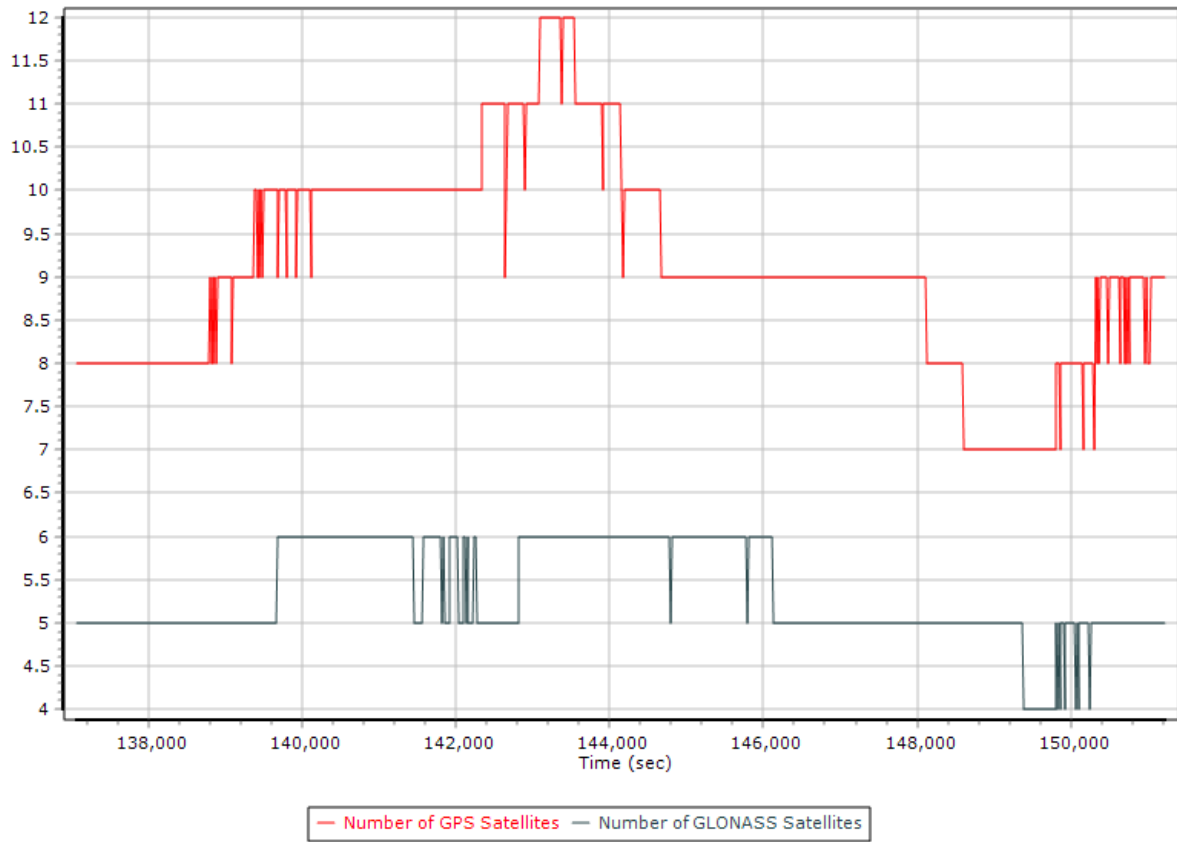
Z:

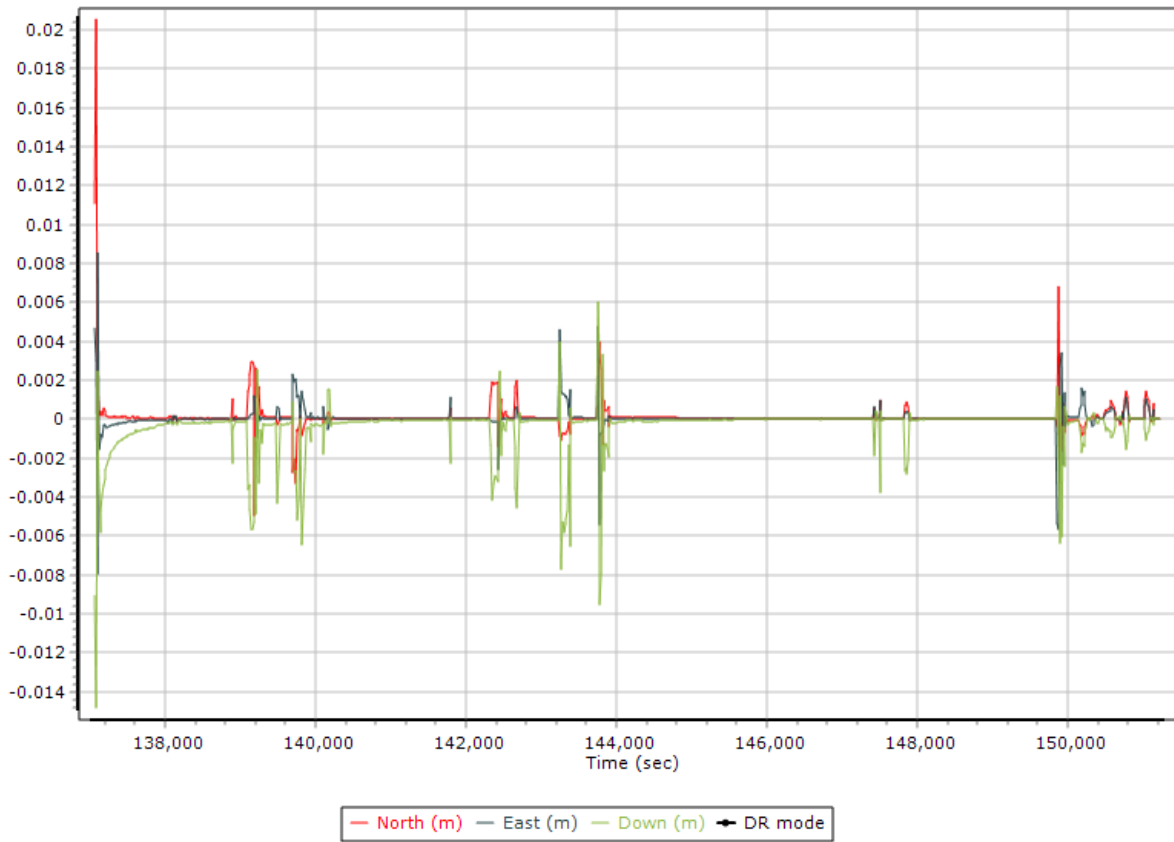
OK Cancel

PDOP









Project Settings [X]

- General Information
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 - Timing**
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LIDAR
- SAR

Timing

Start: 134244.000
 End: 151242.000

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

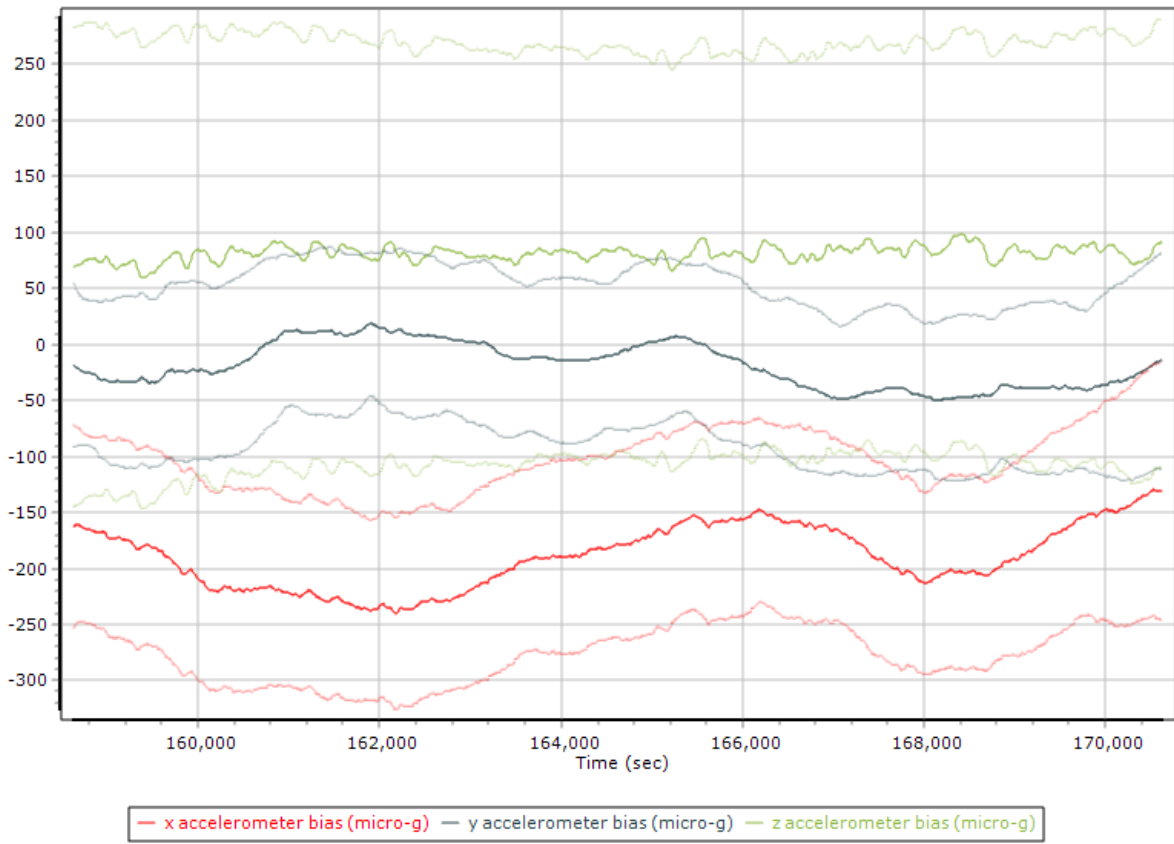
Processable Time Windows

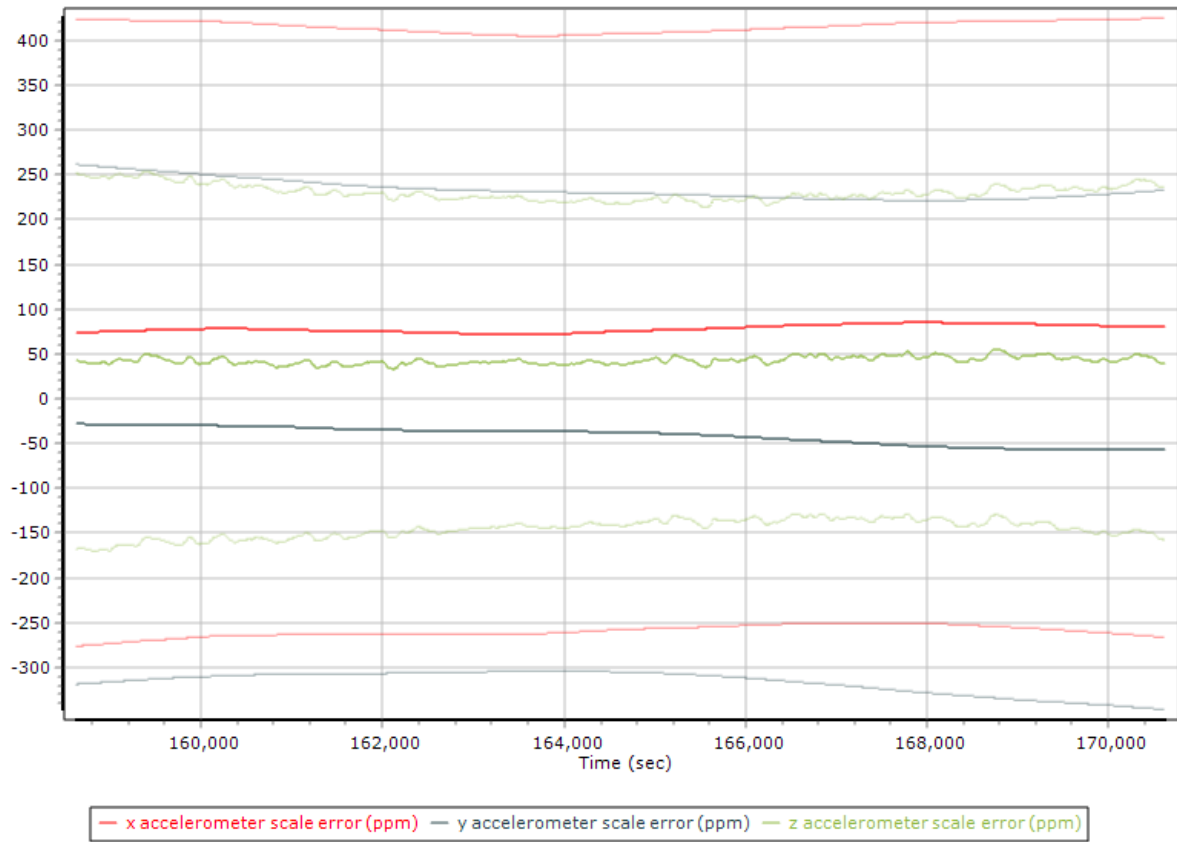
Start after launch Wait Time: 4.000 sec

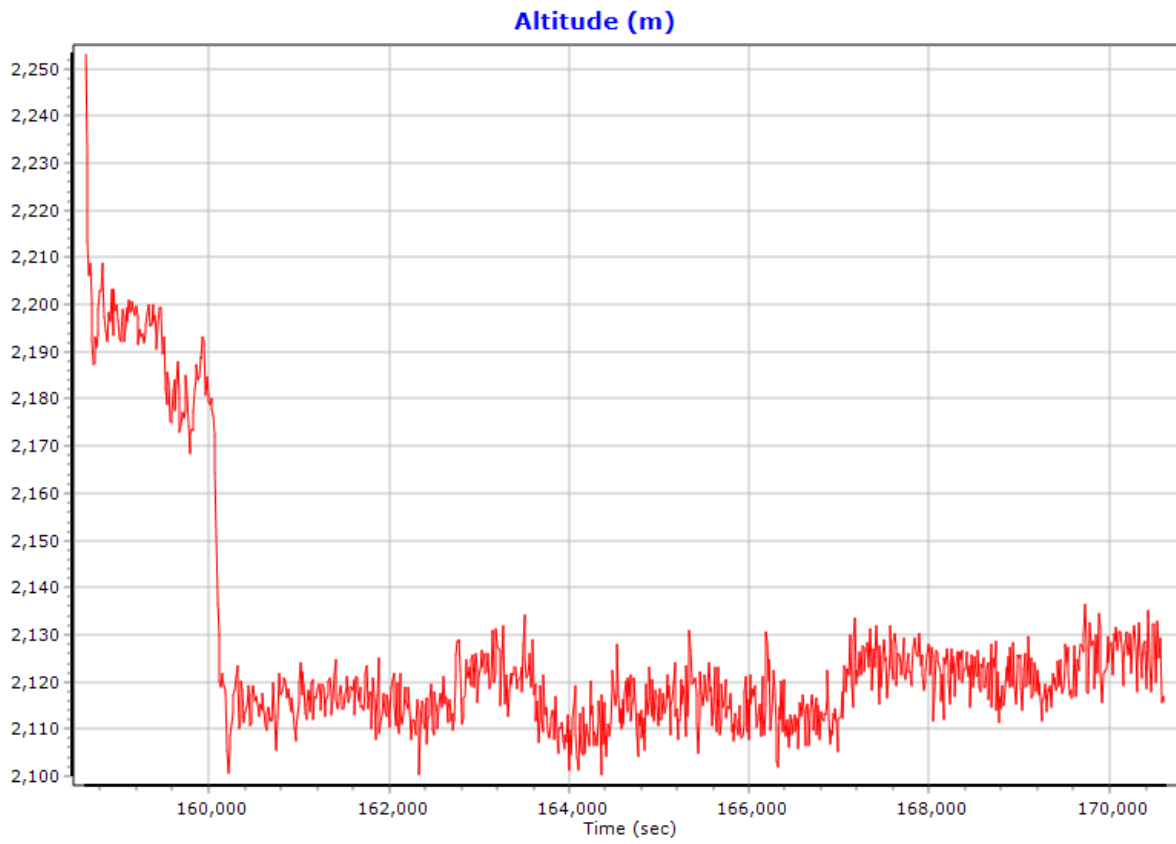
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	134244.000	151242.000	16998.000	End of file

OK Cancel

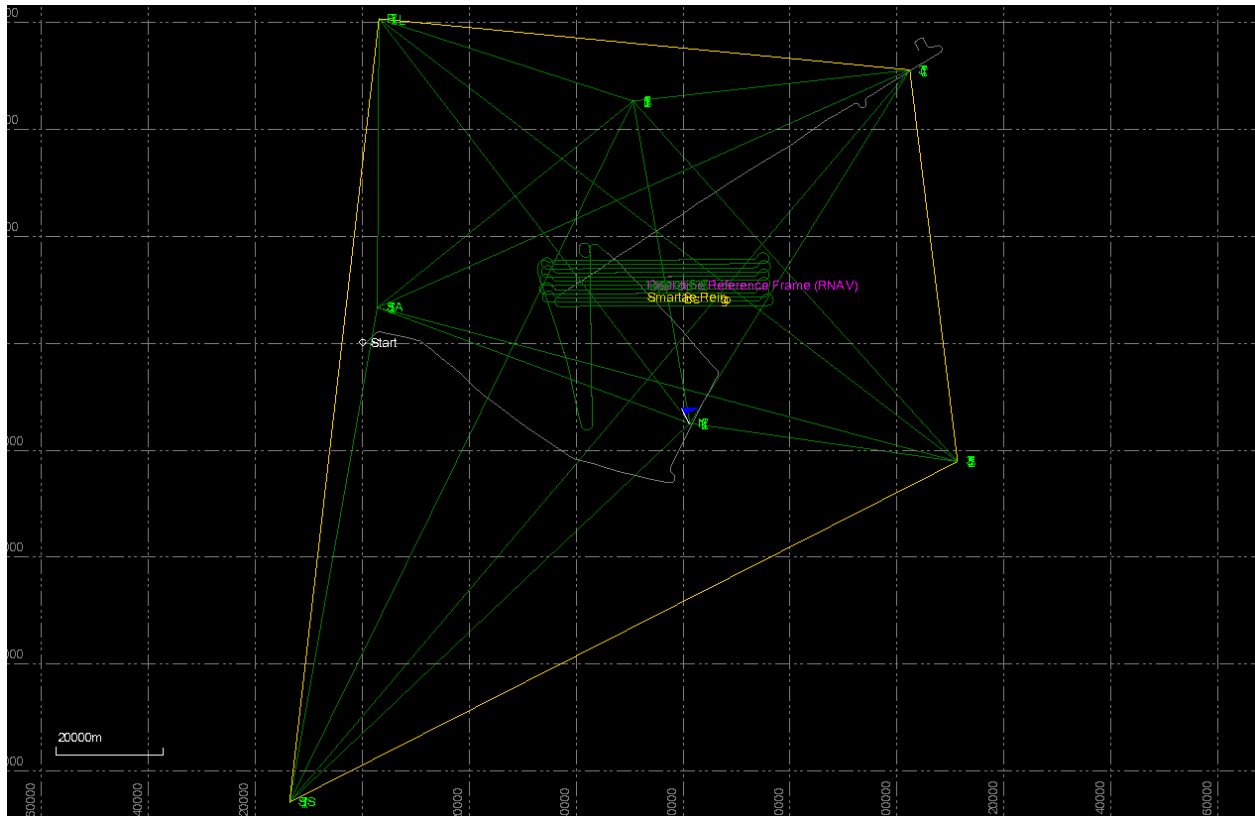
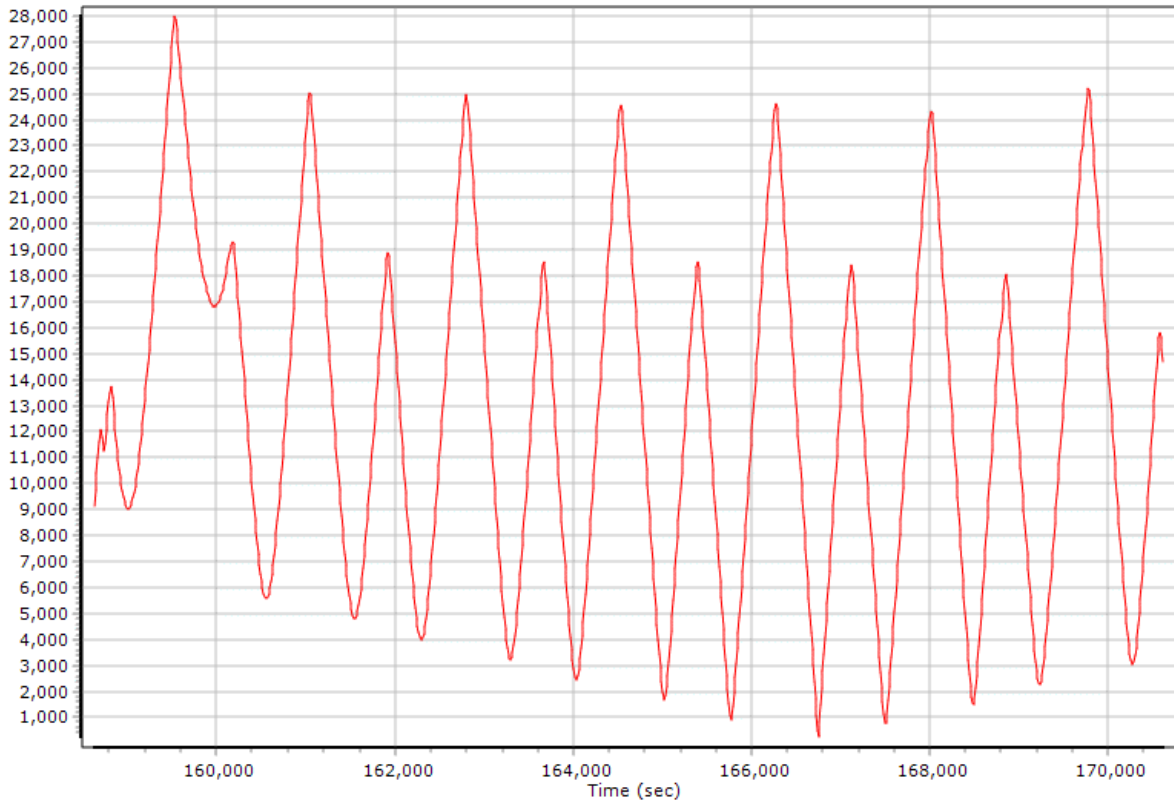
CAU18071B

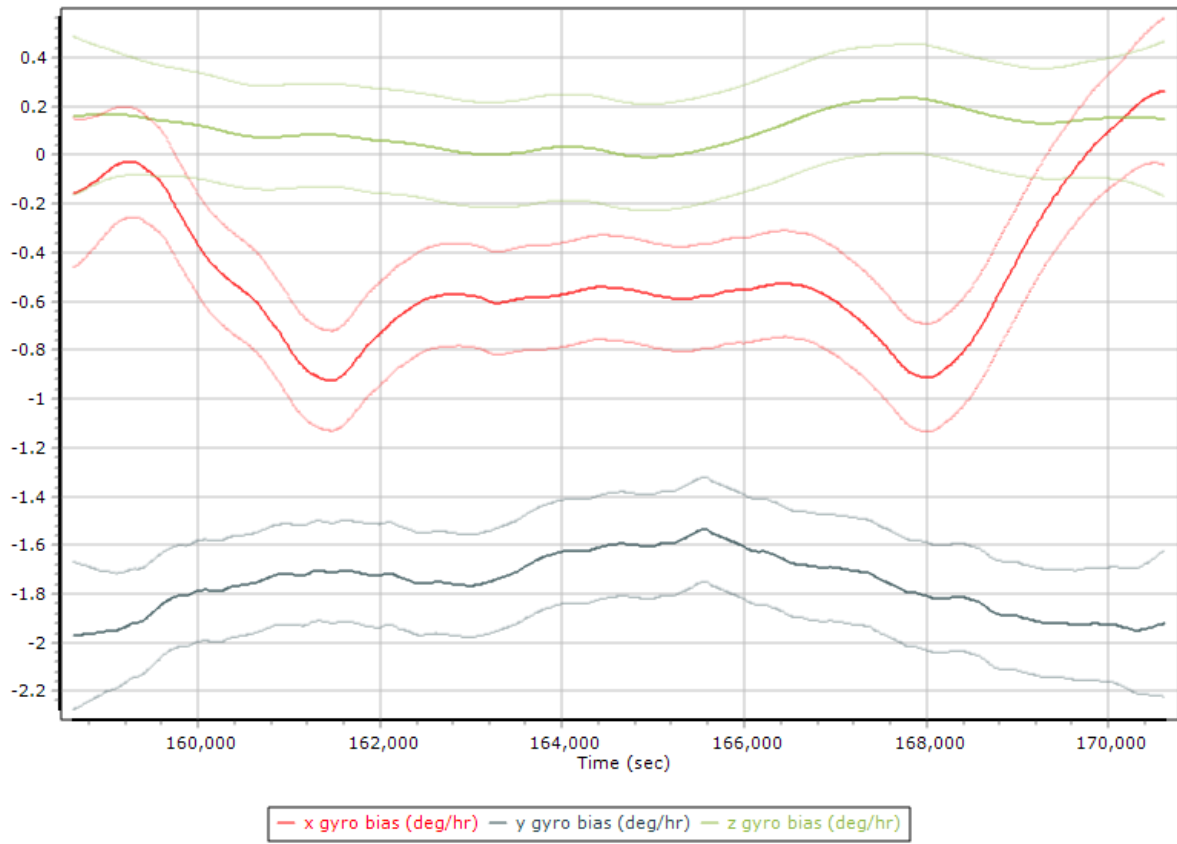


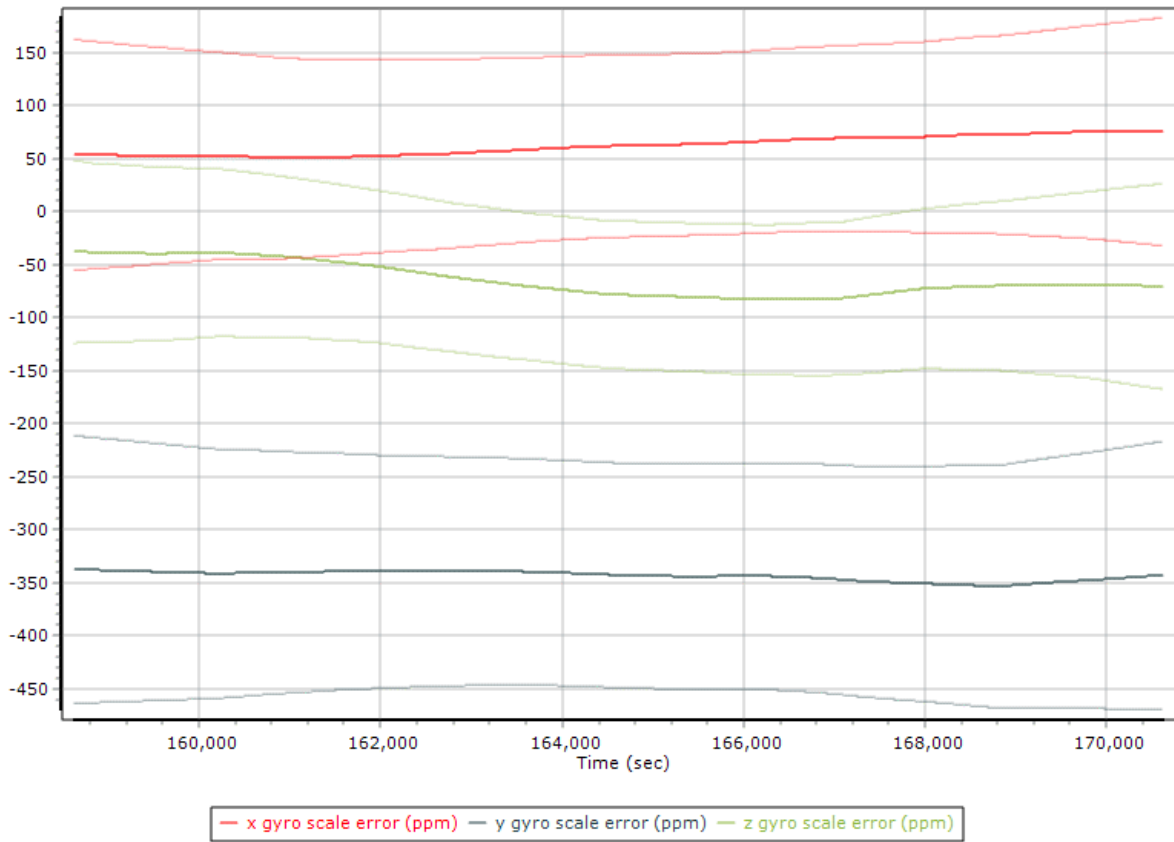




Baseline Length (m)







Project Settings

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

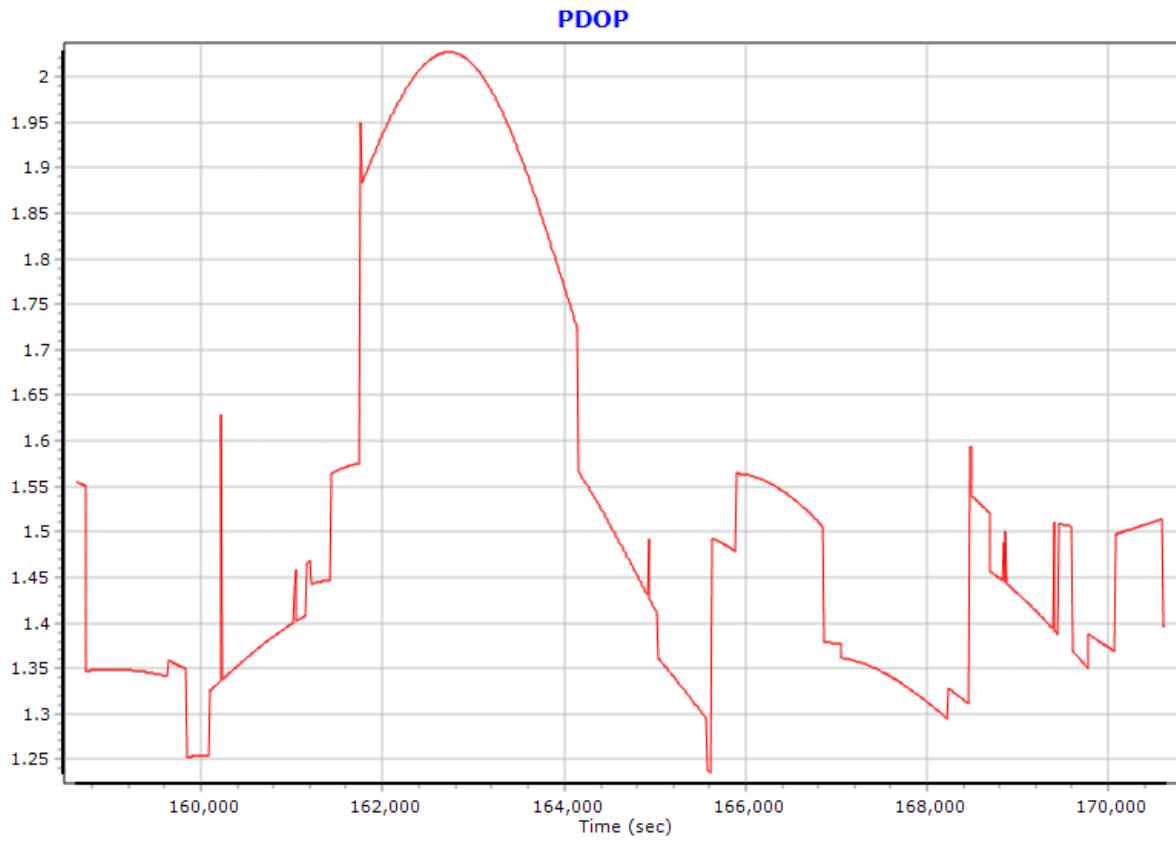
Aircraft to Reference Mounting Angles

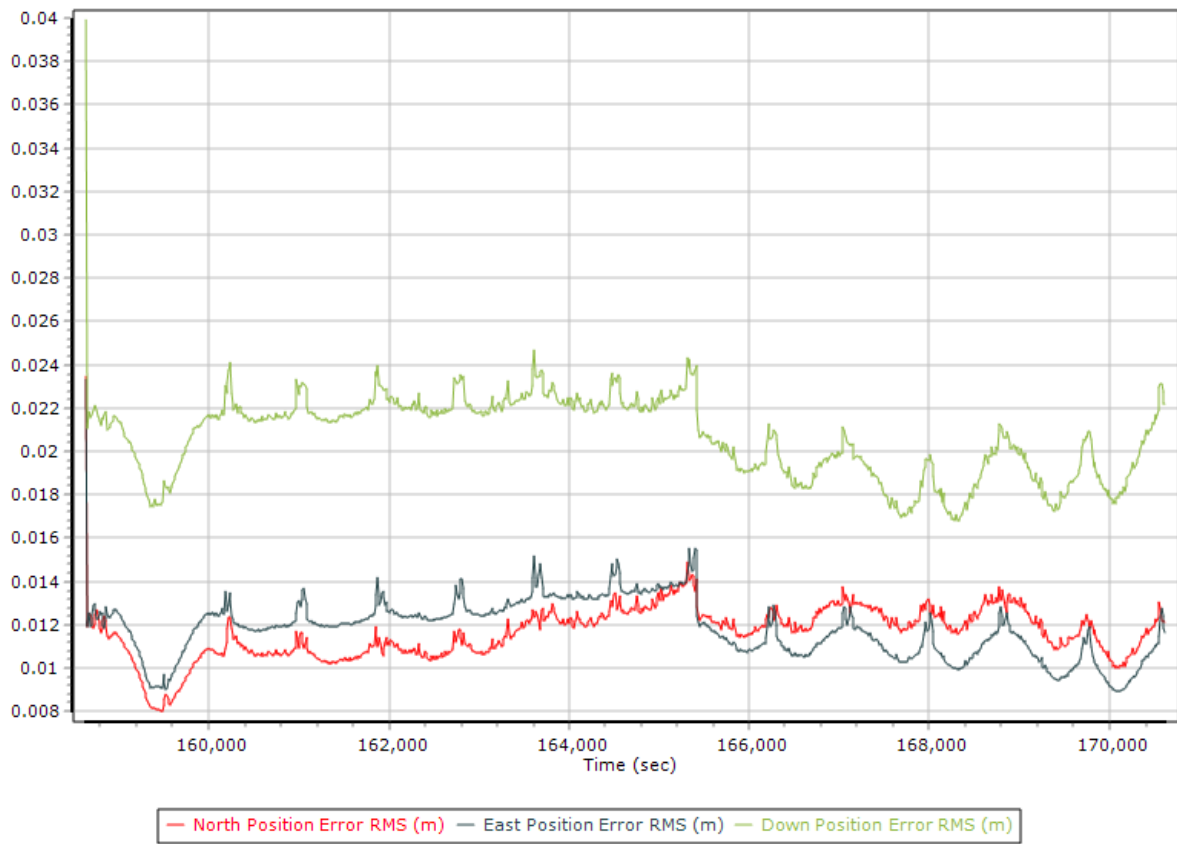
X:

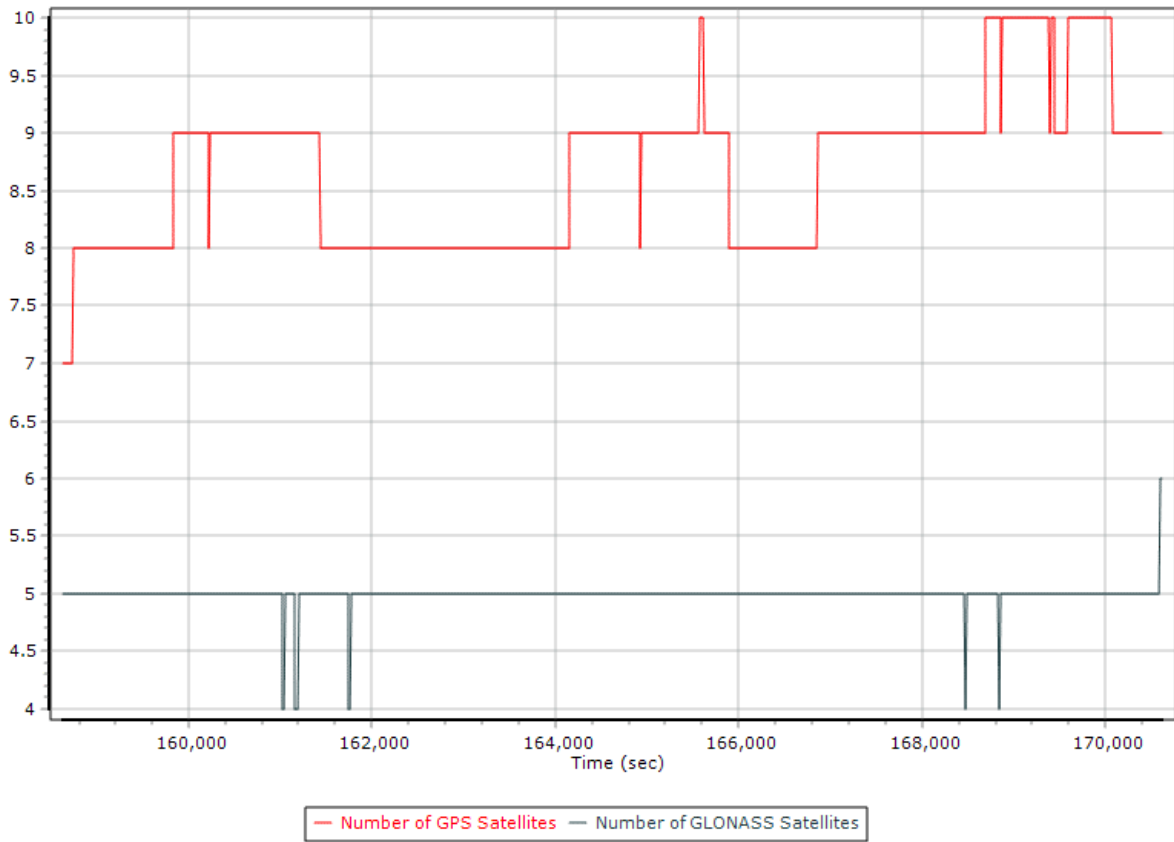
Y:

Z:

OK Cancel









Project Settings

- 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: 155421.000
End: 172544.000

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

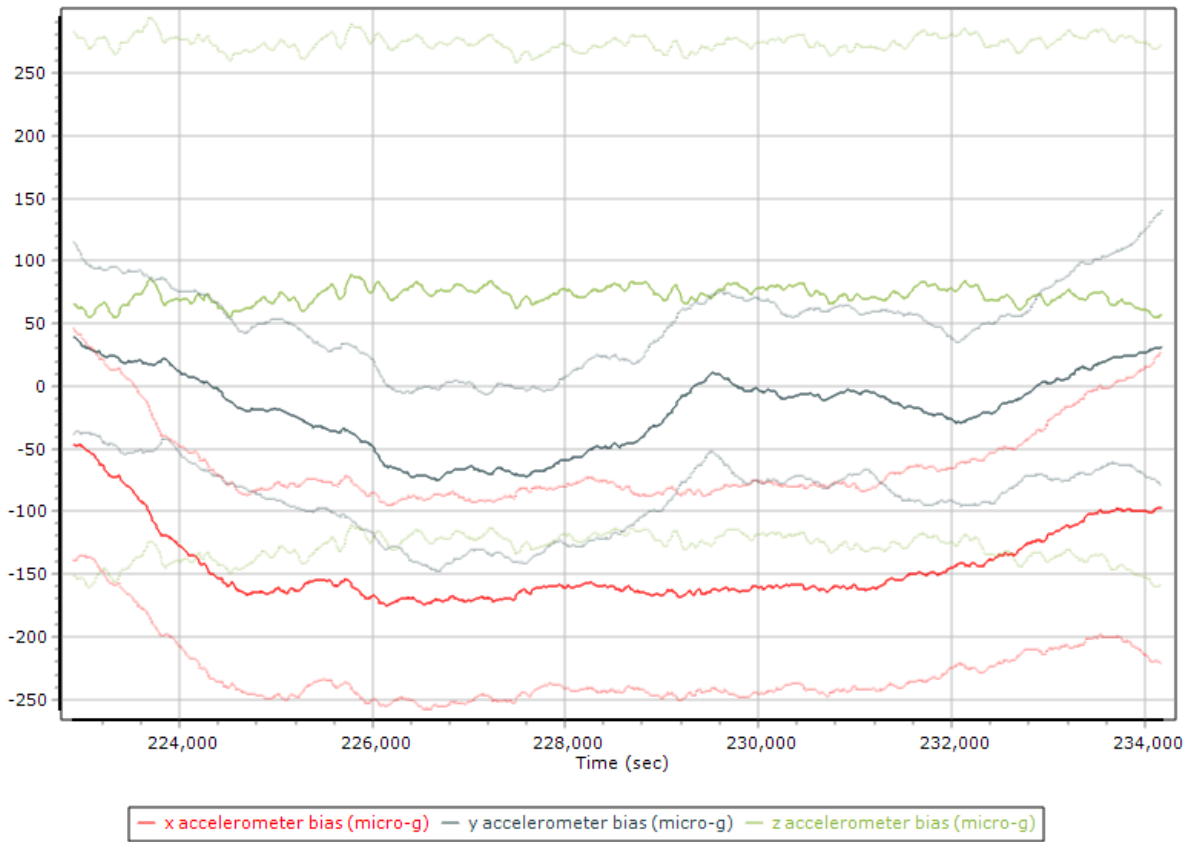
Processable Time Windows

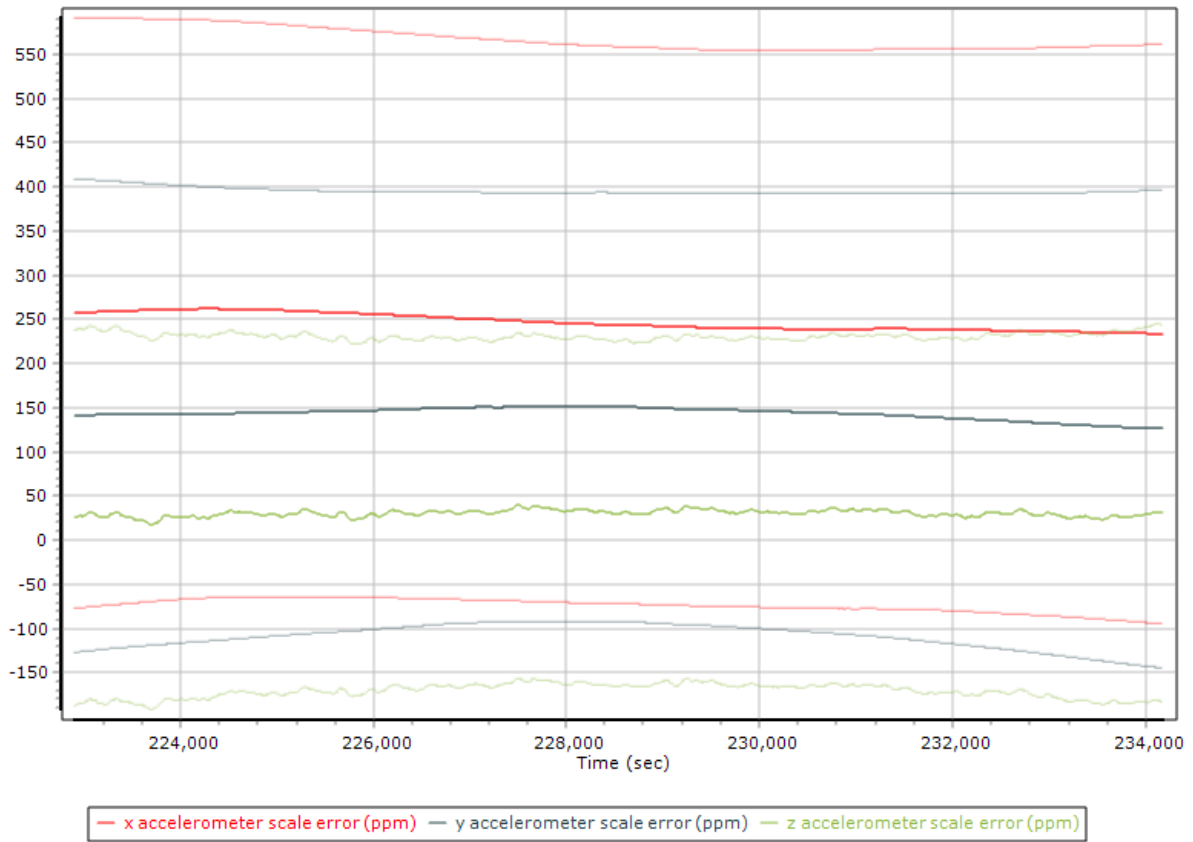
Start after launch Wait Time: 4.000 sec

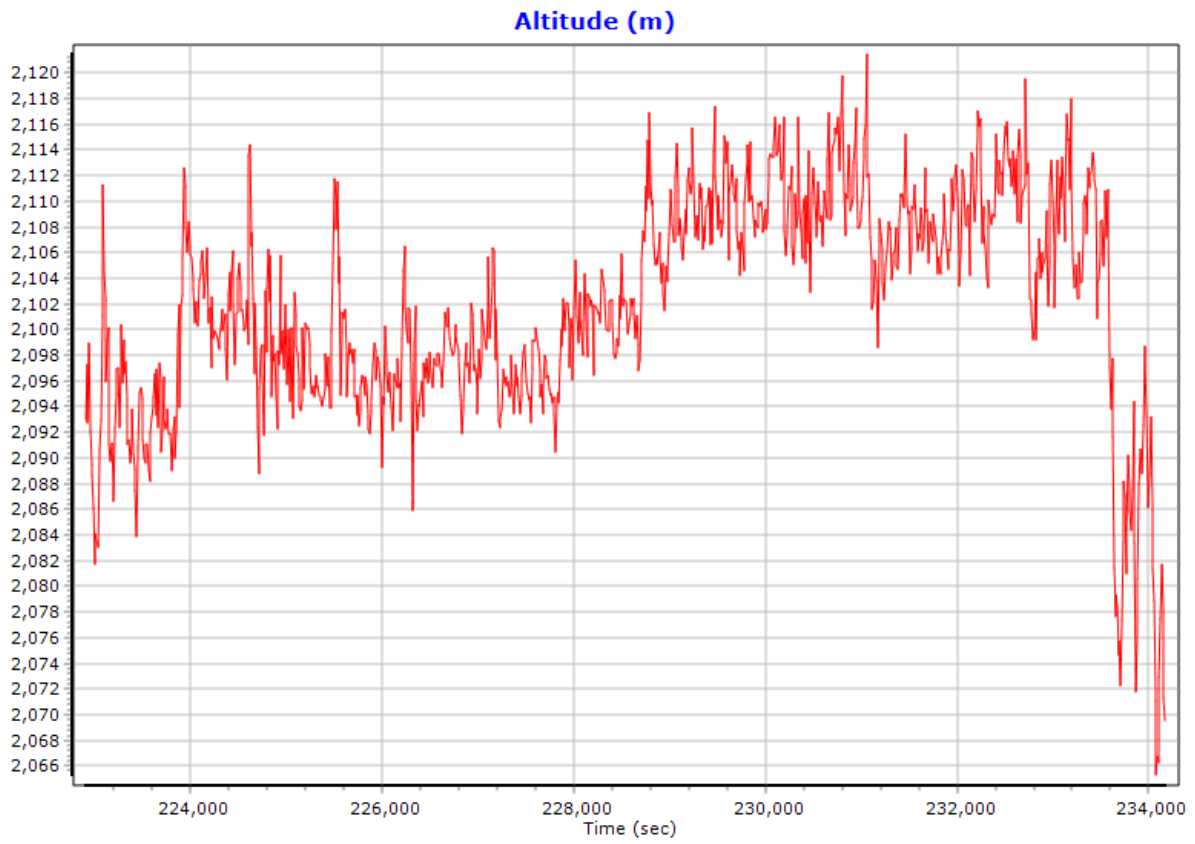
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	155421.000	172544.000	17123.000	End of file

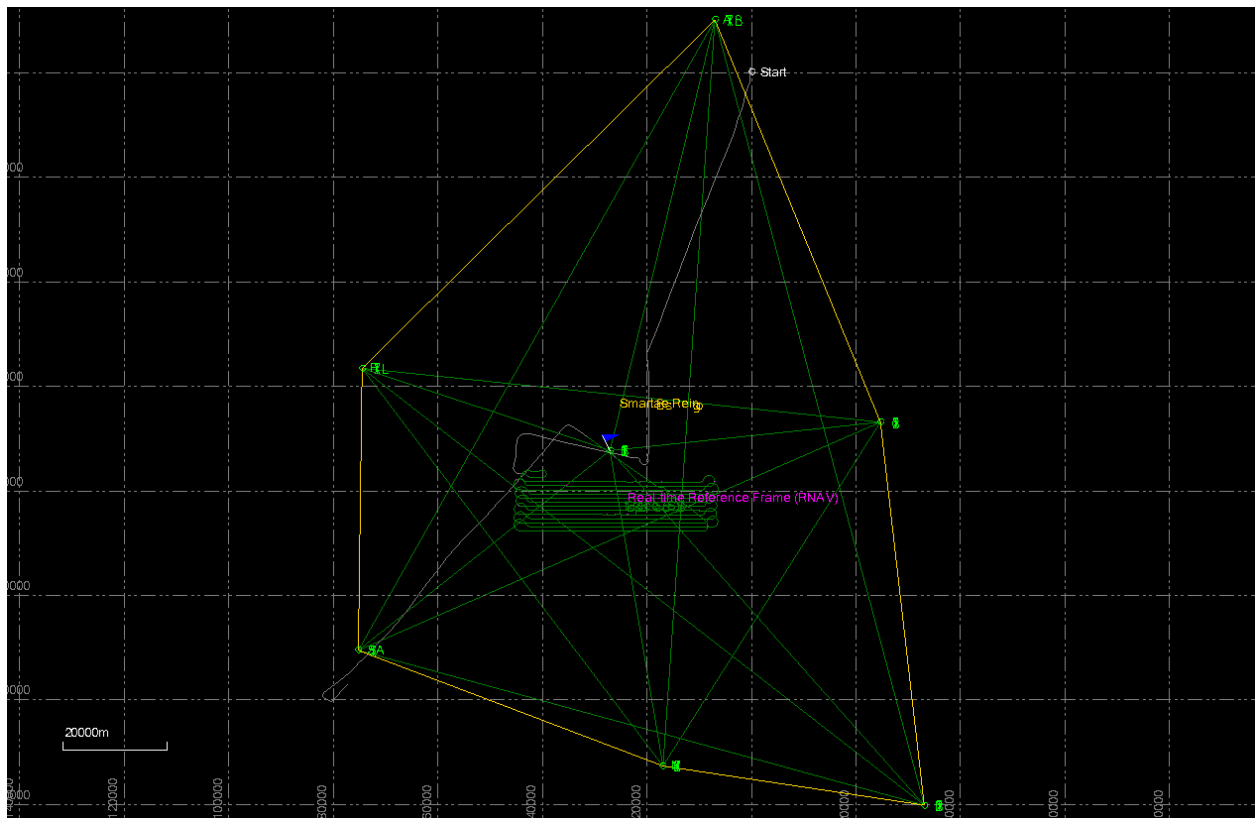
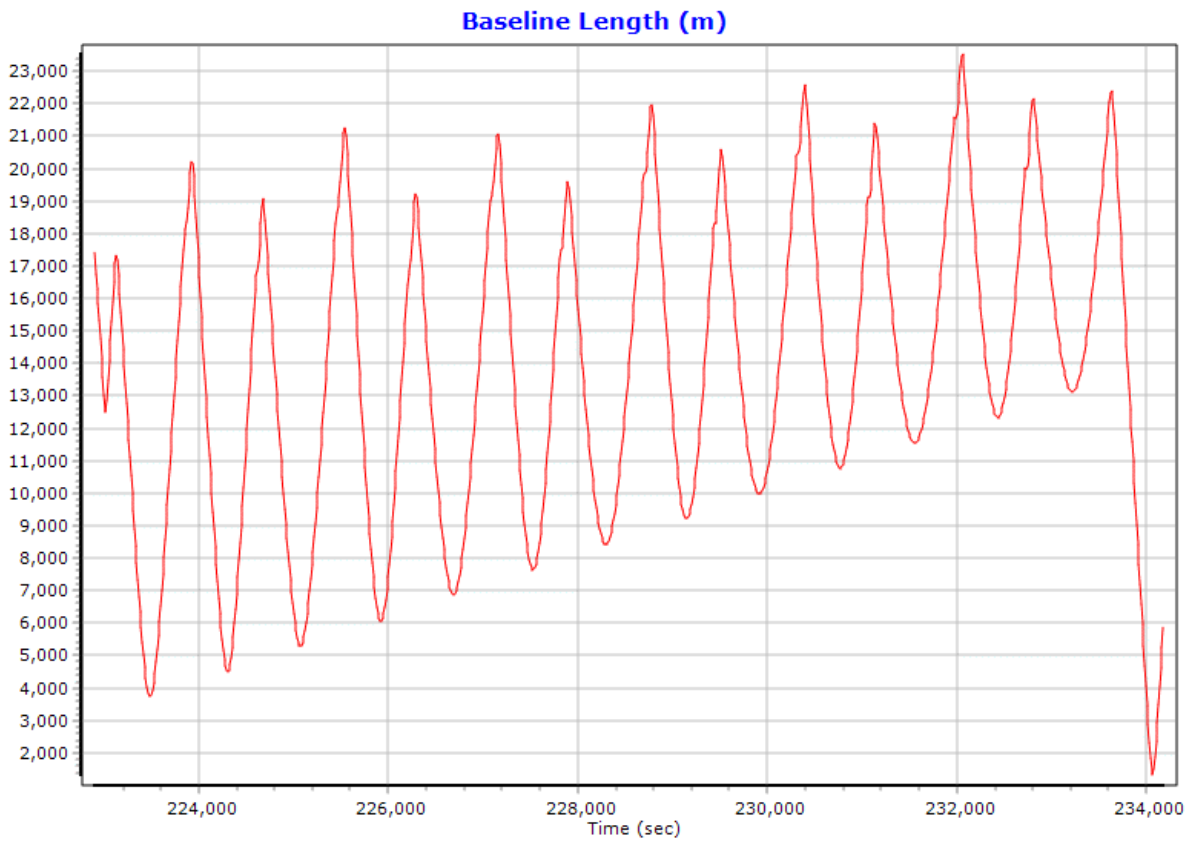
OK Cancel

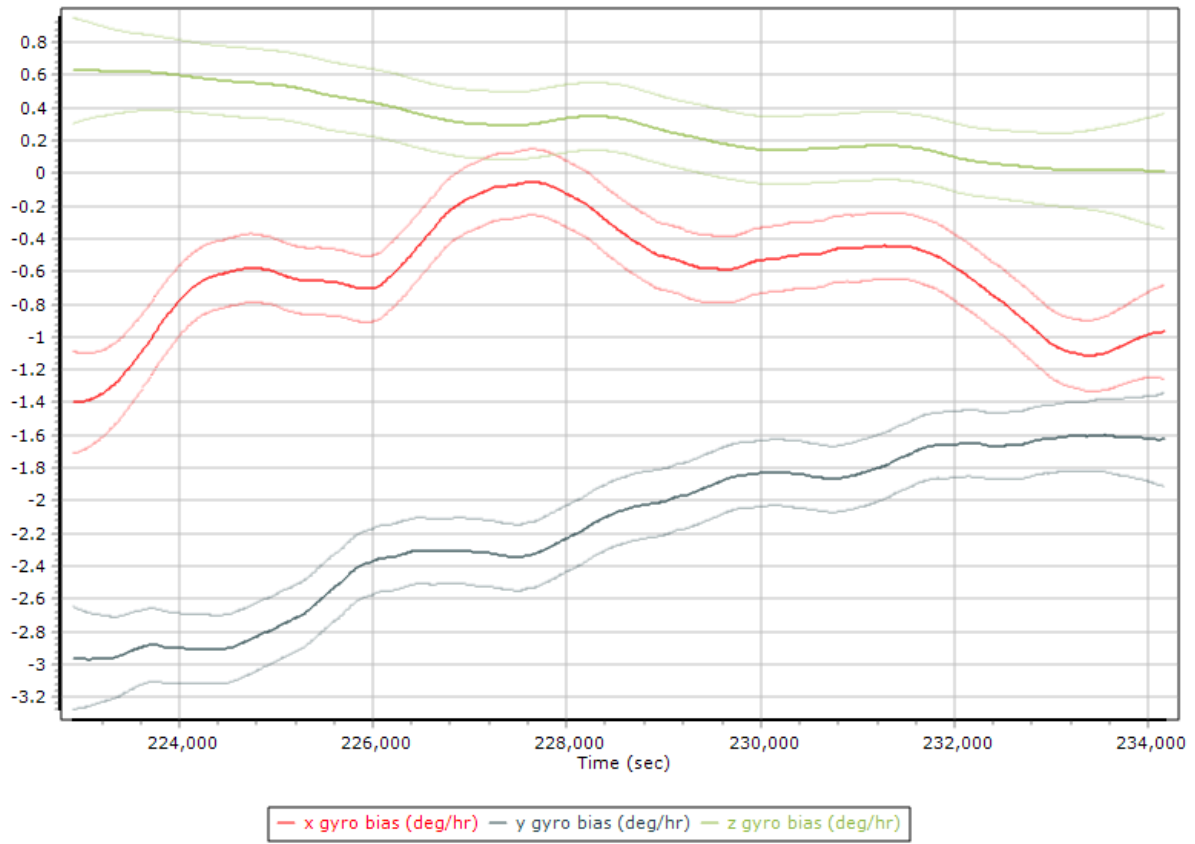
CAU18072A

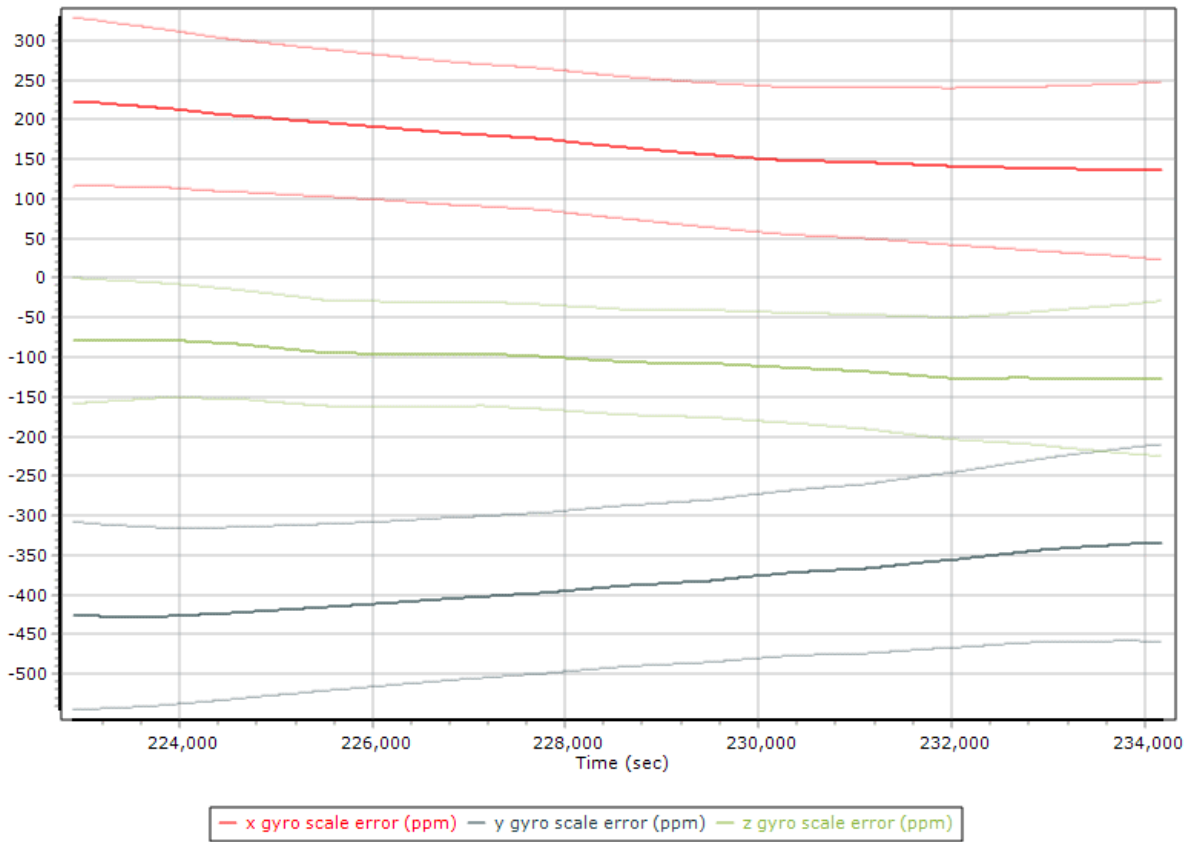












Project Settings ✕

- General Information
- Units
- View
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 - Timing
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 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

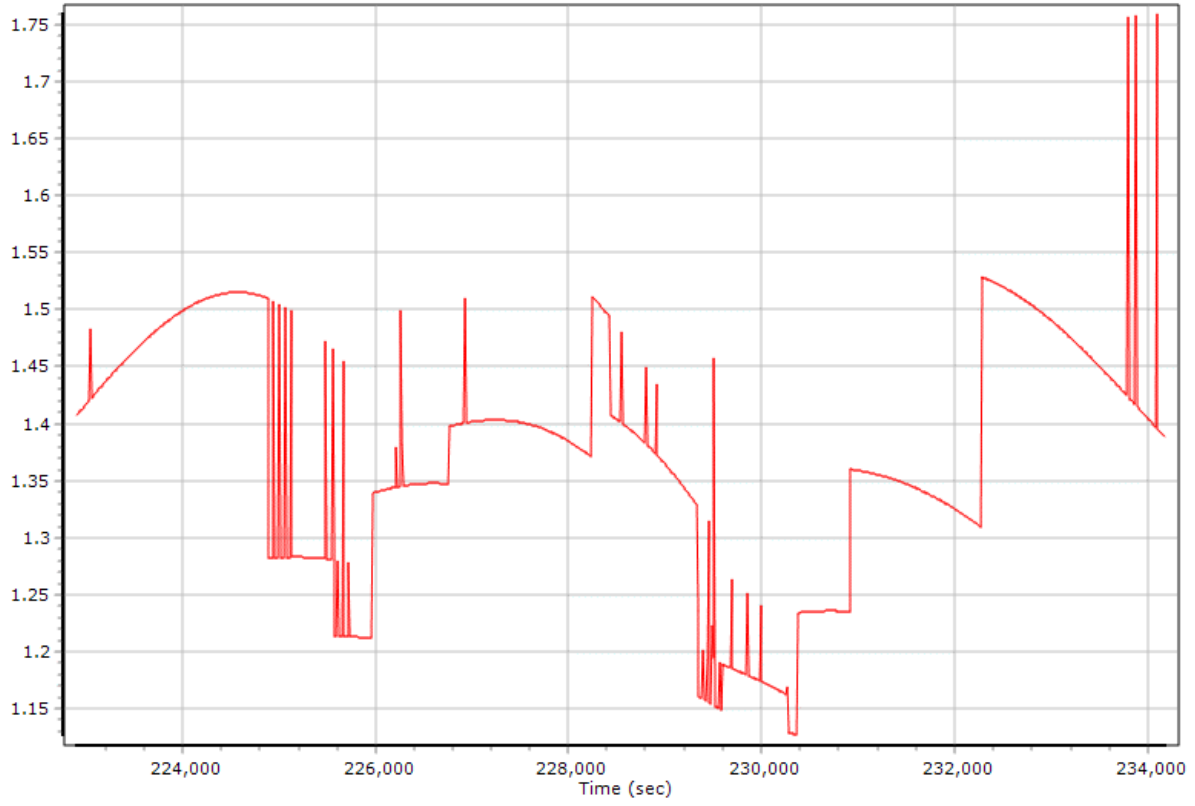
Aircraft to Reference Mounting Angles

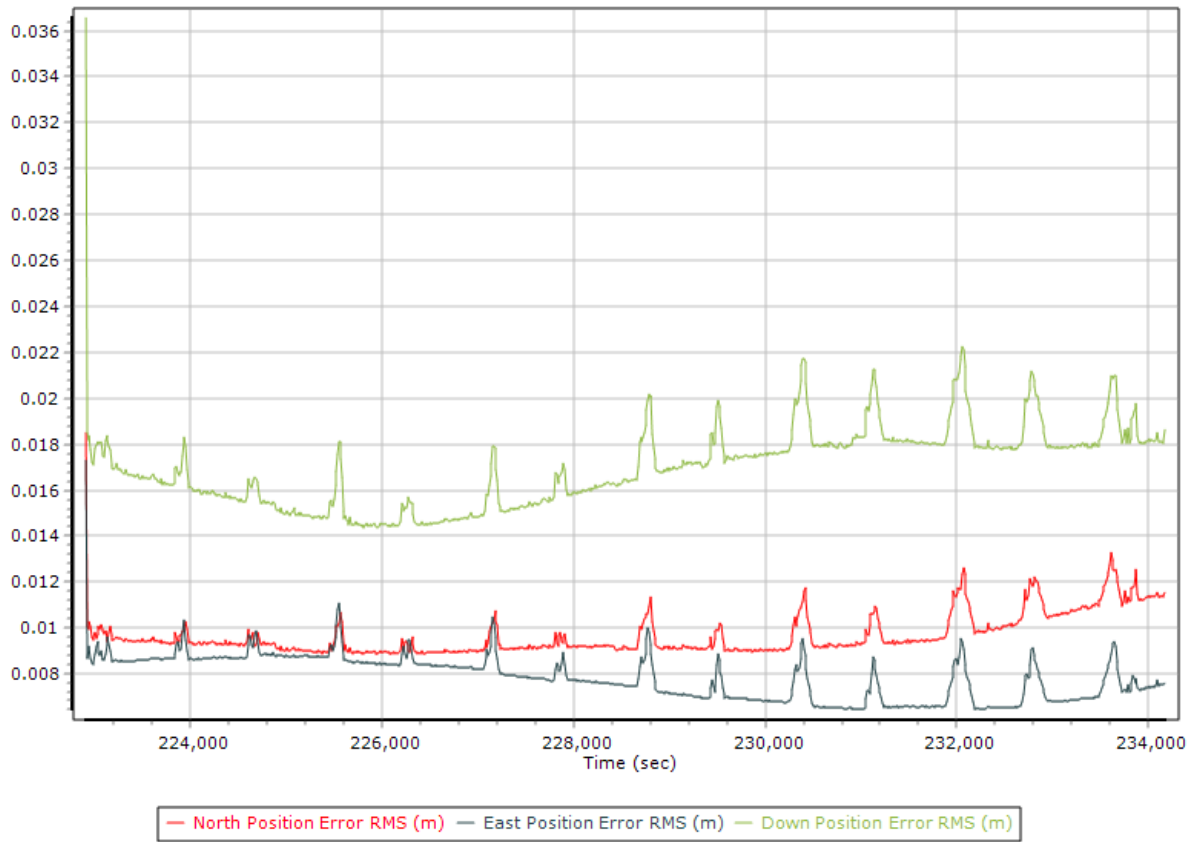
X:

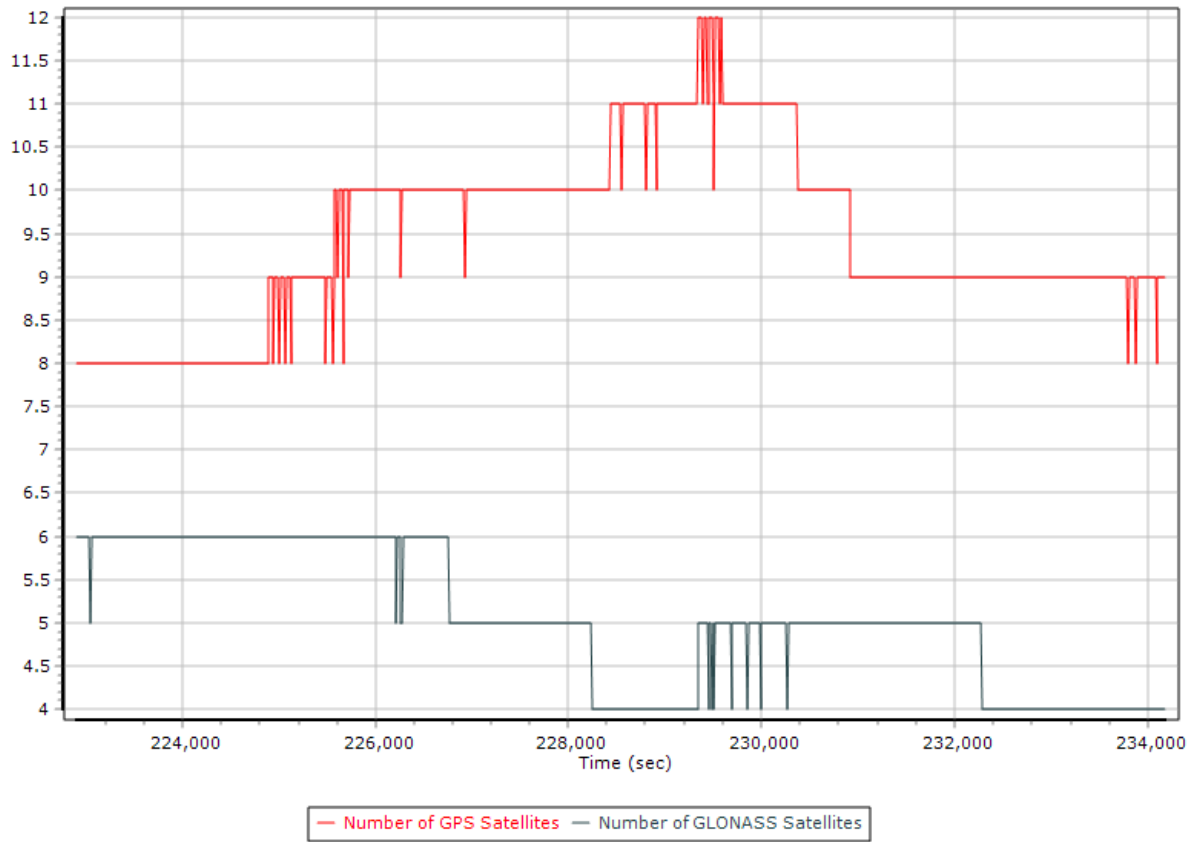
Y:

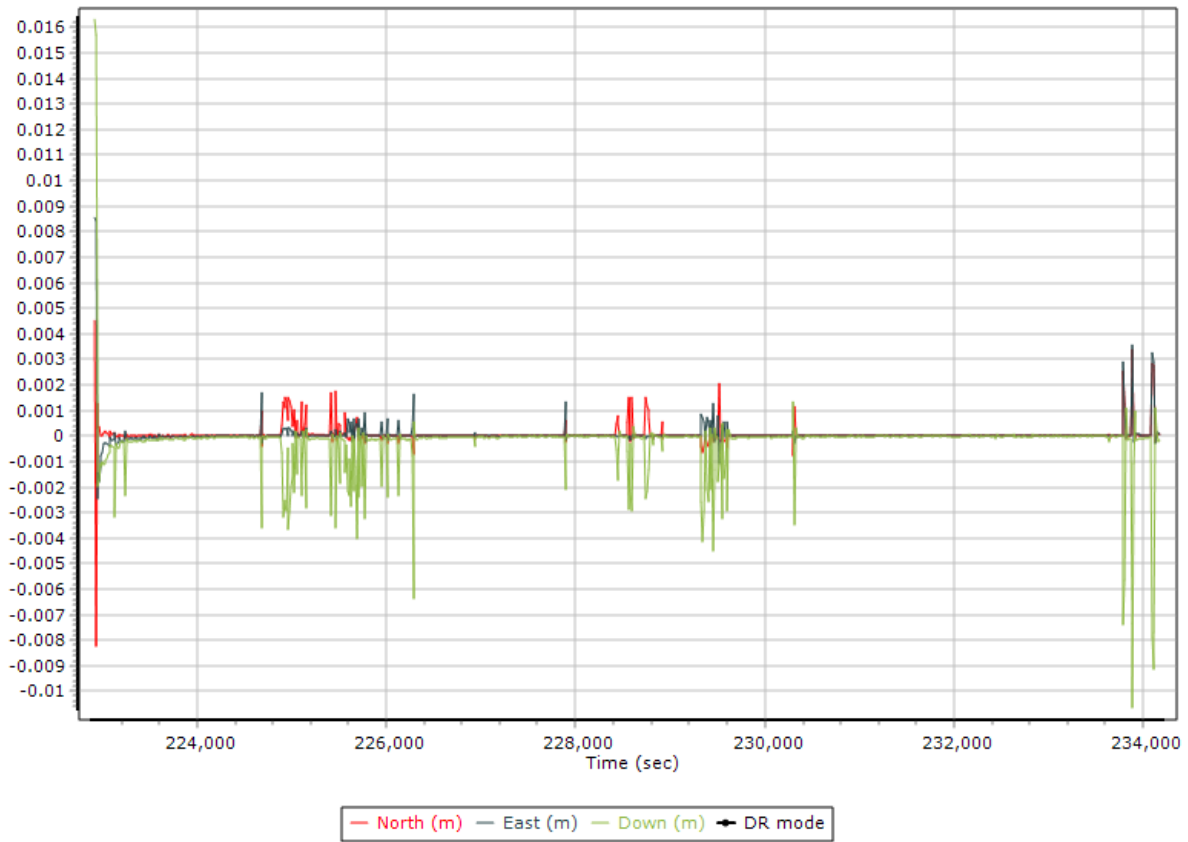
Z:

PDOP









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: 219844.000
 End: 235730.000
 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

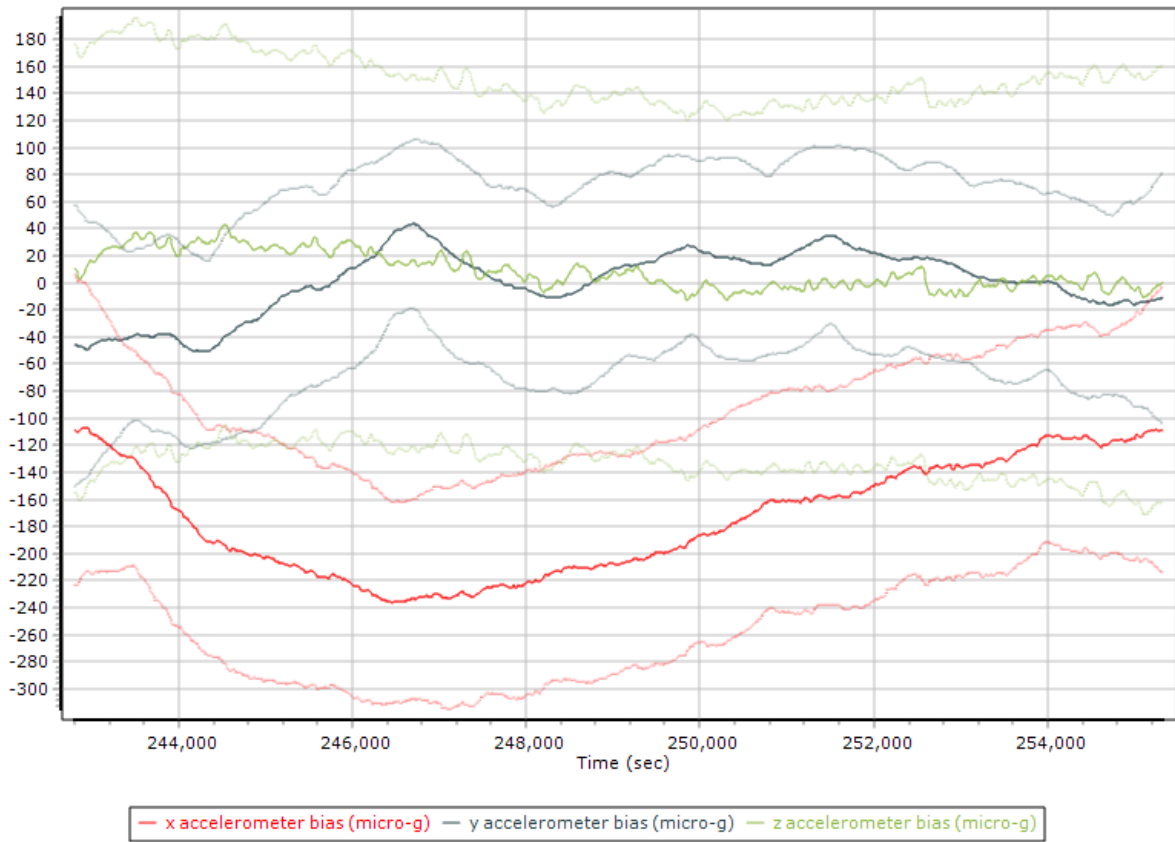
Processable Time Windows

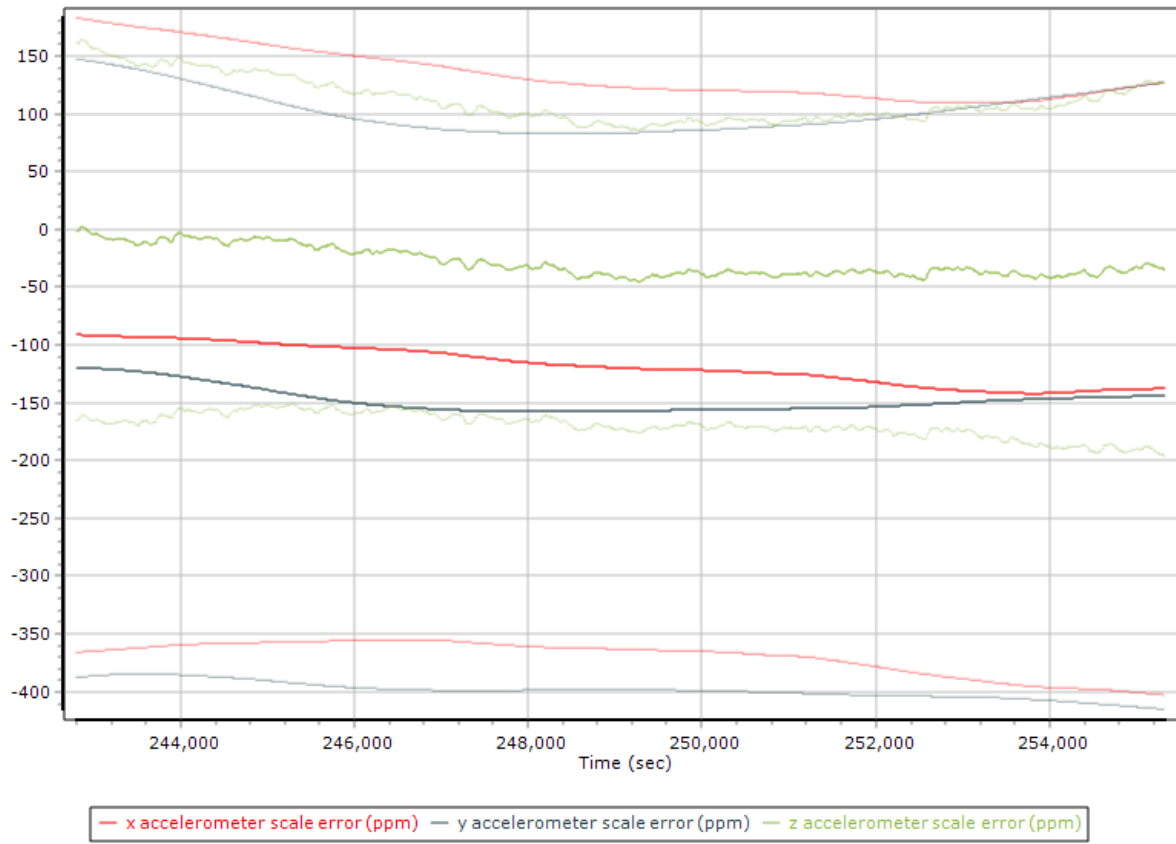
Start after launch Wait Time: 4.000 sec

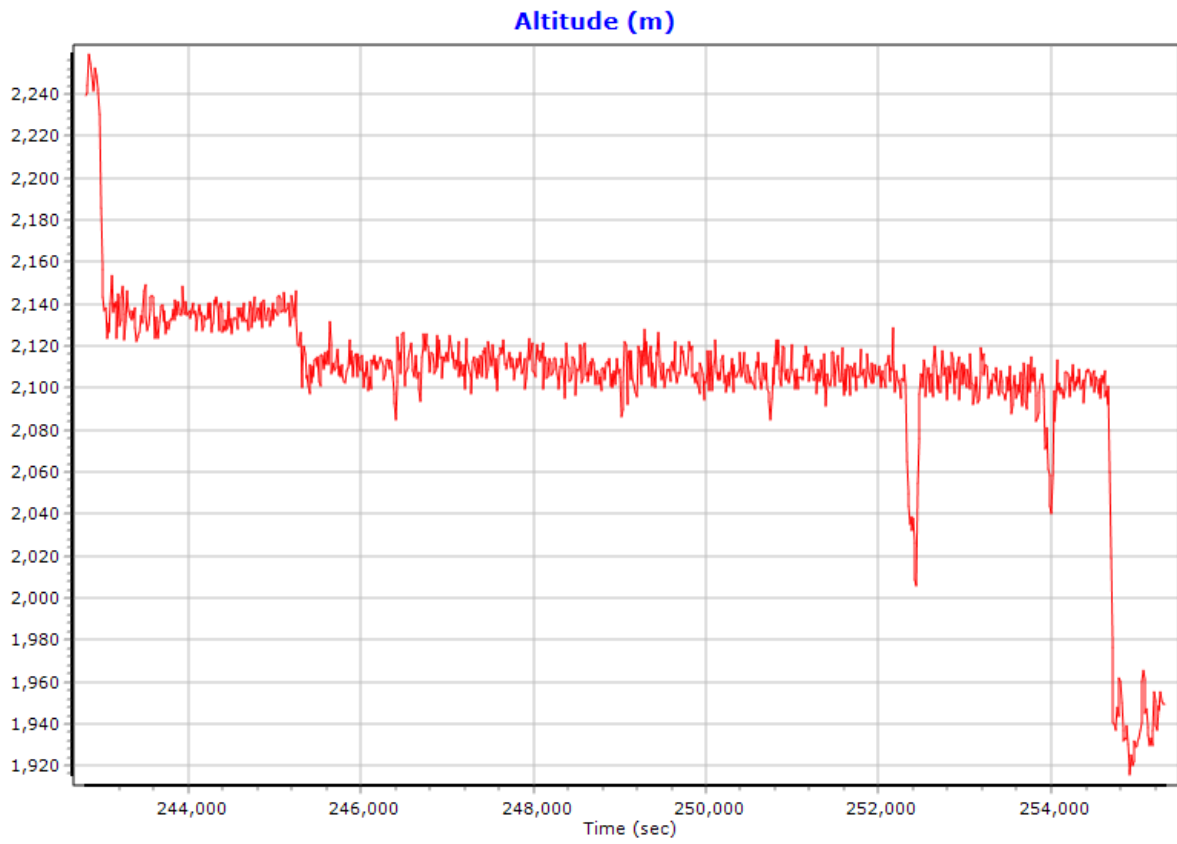
Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/> 219844.000	235730.000	15886.000	End of file

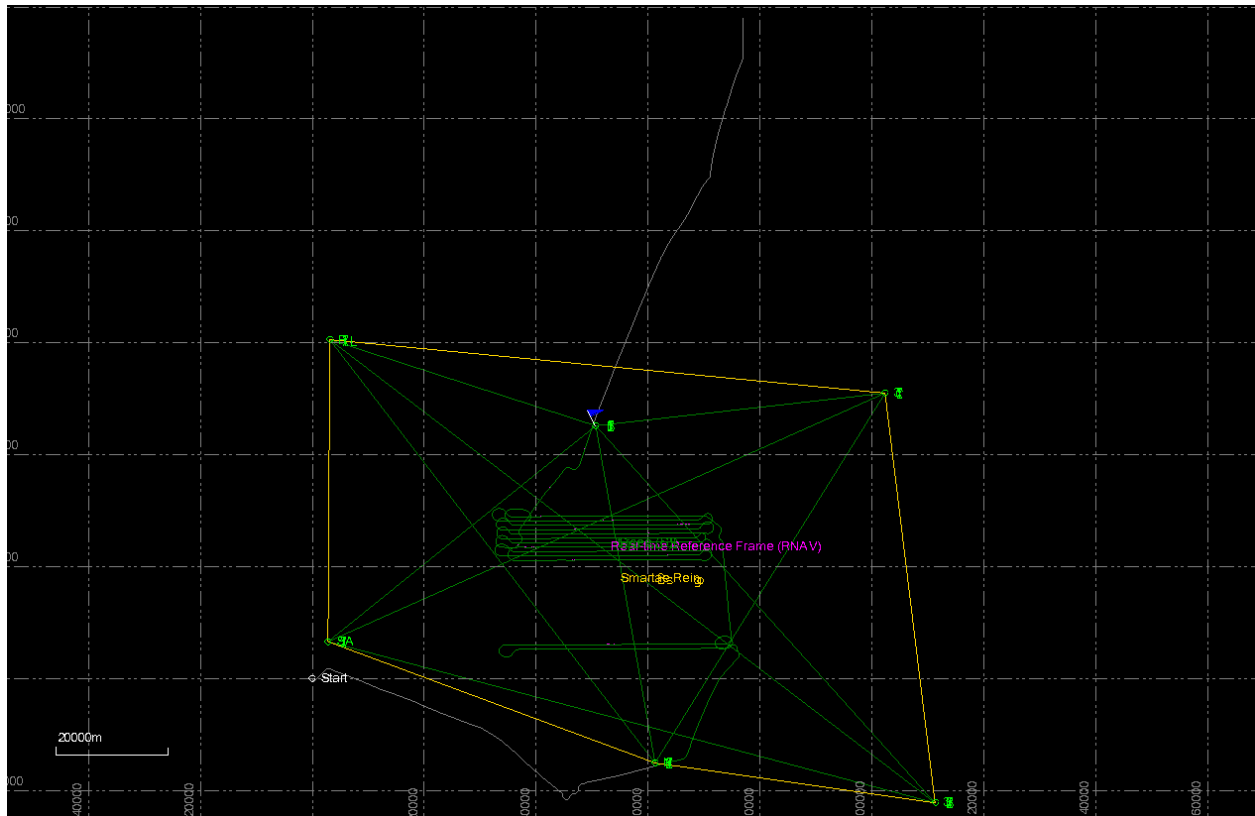
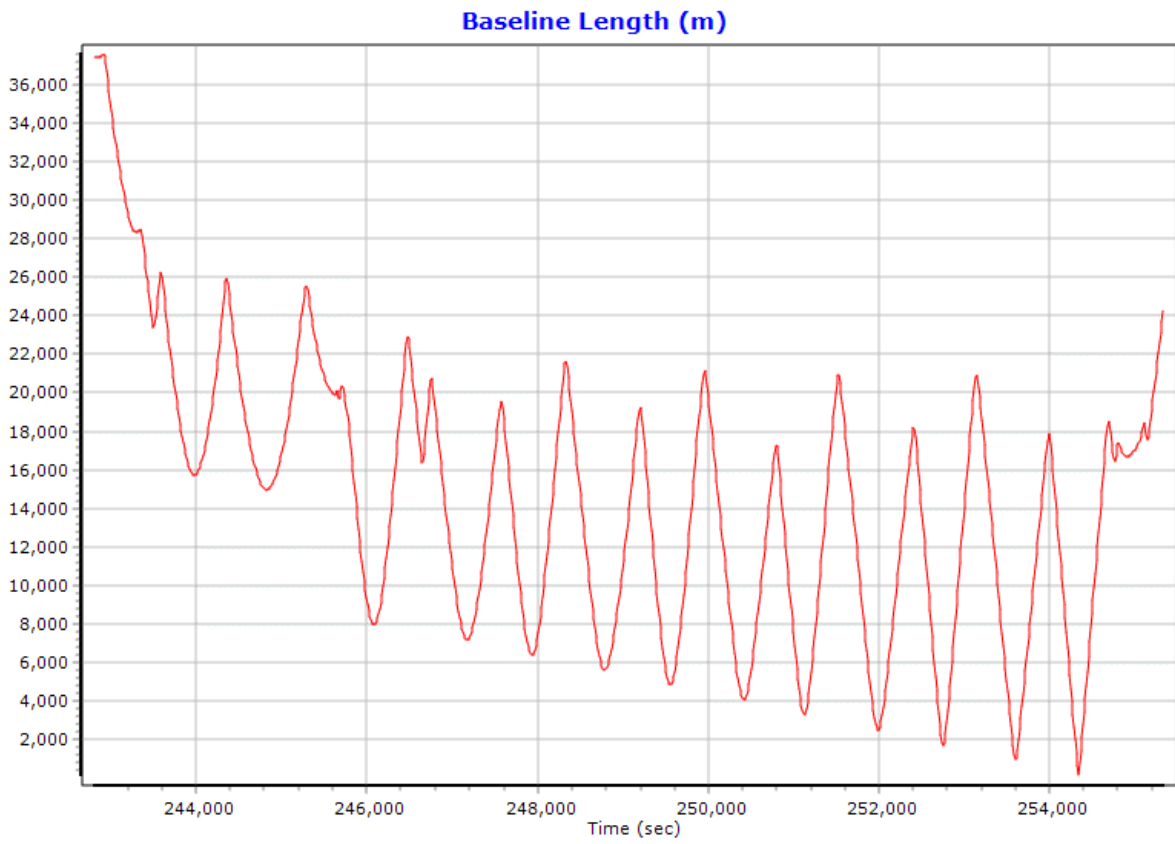
OK Cancel

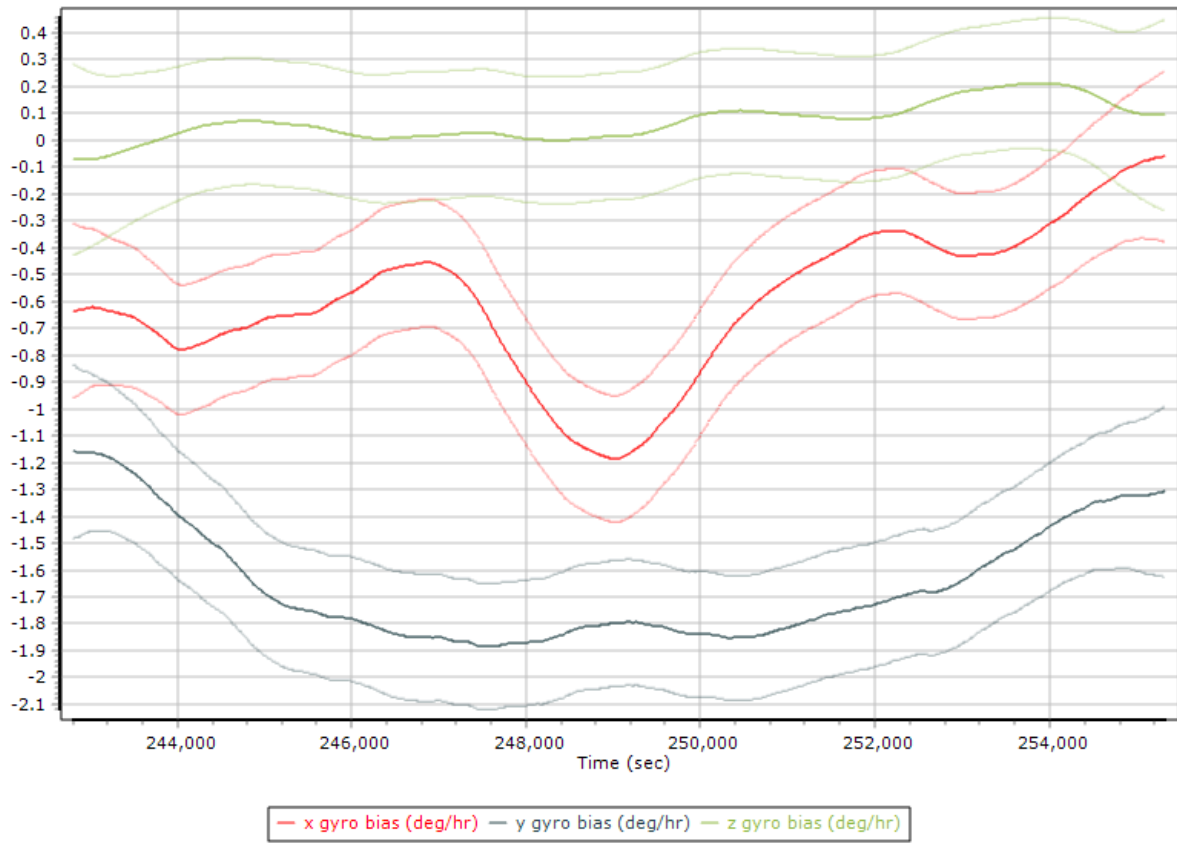
CAU18072B

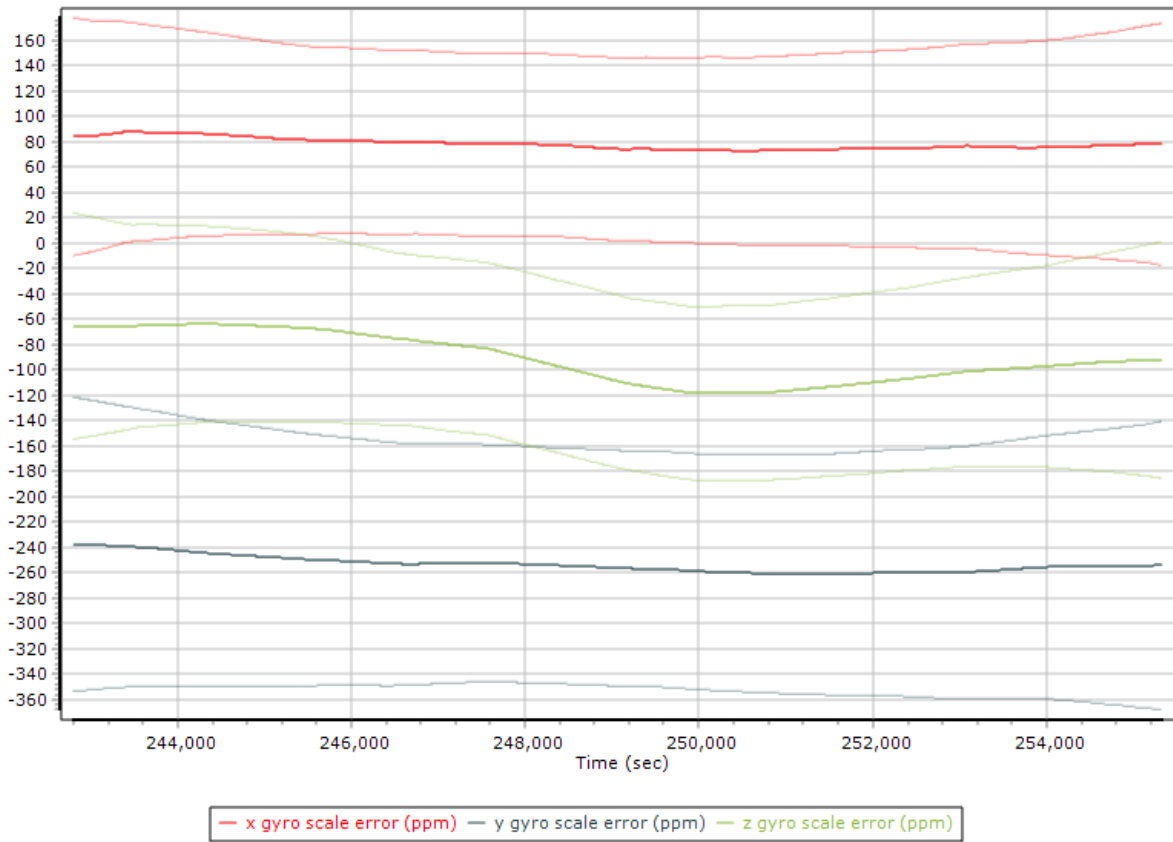












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation: (Selected)

<3cm 10cm 50cm 1m 10m

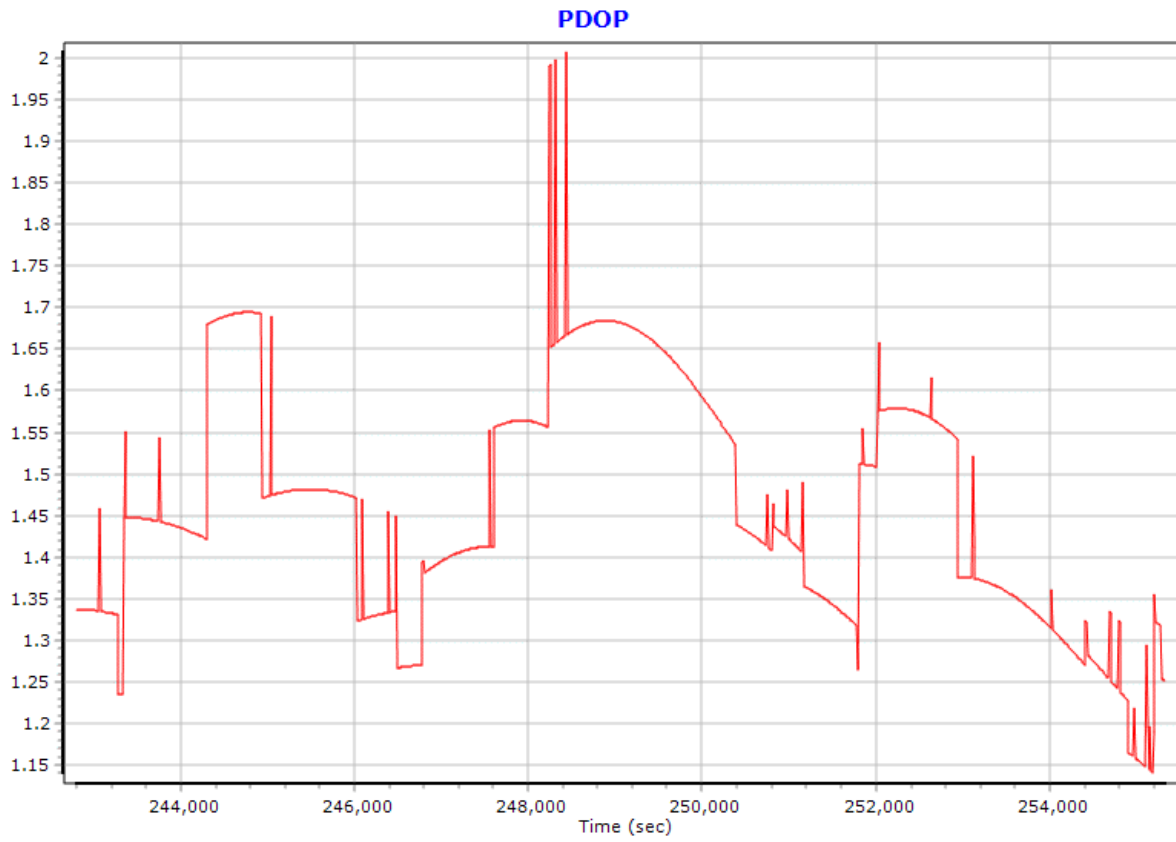
Aircraft to Reference Mounting Angles

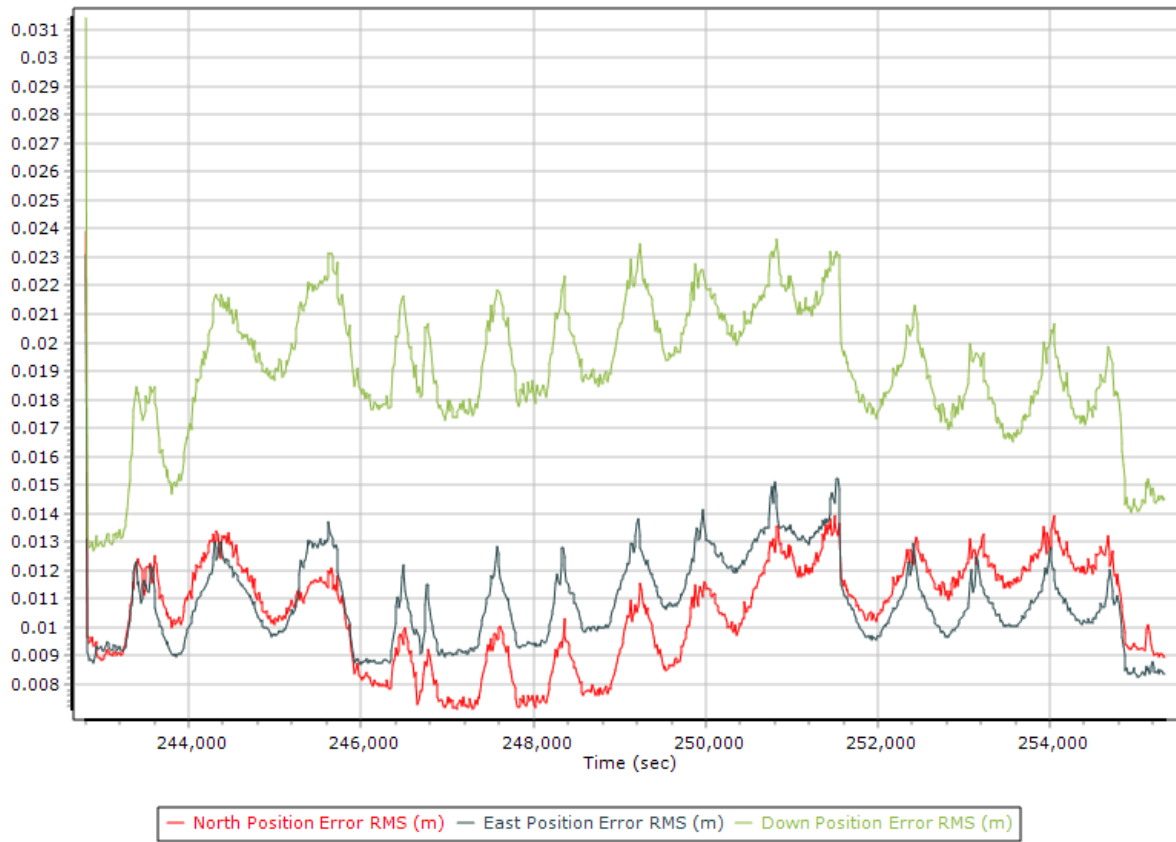
X:

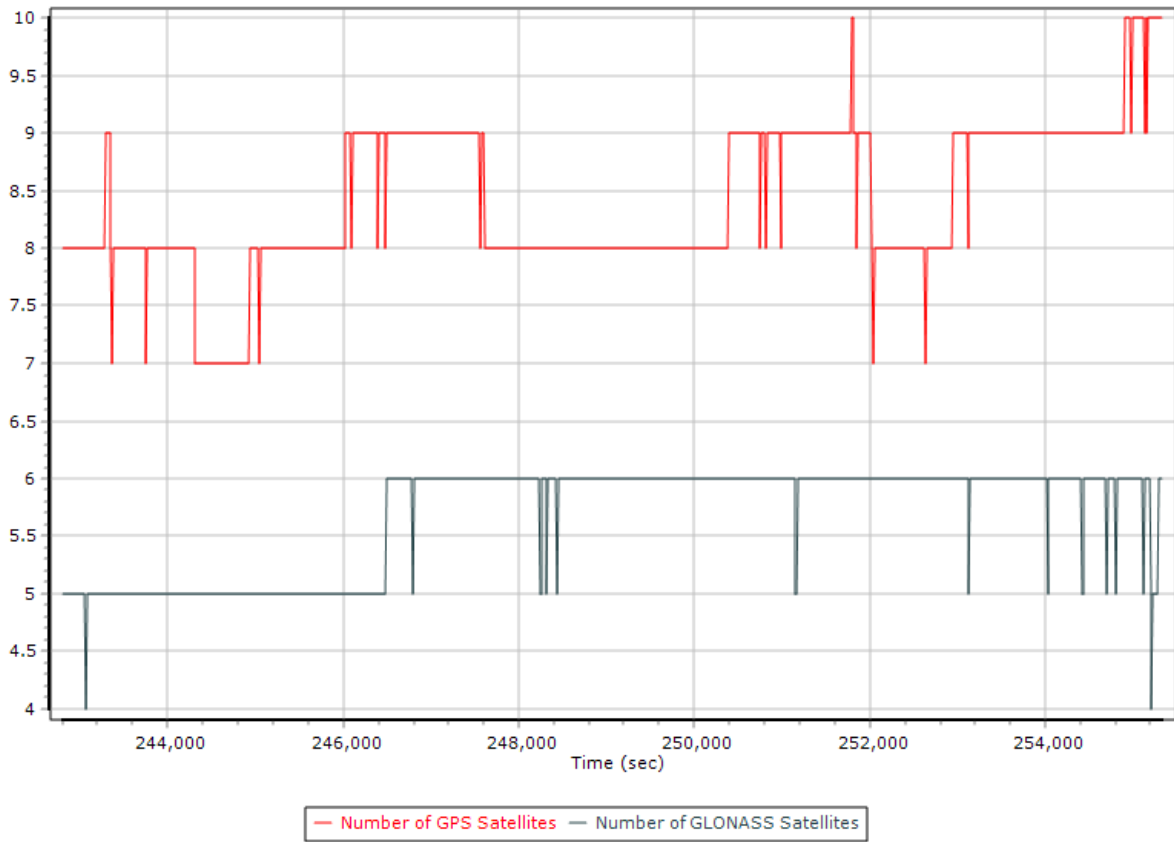
Y:

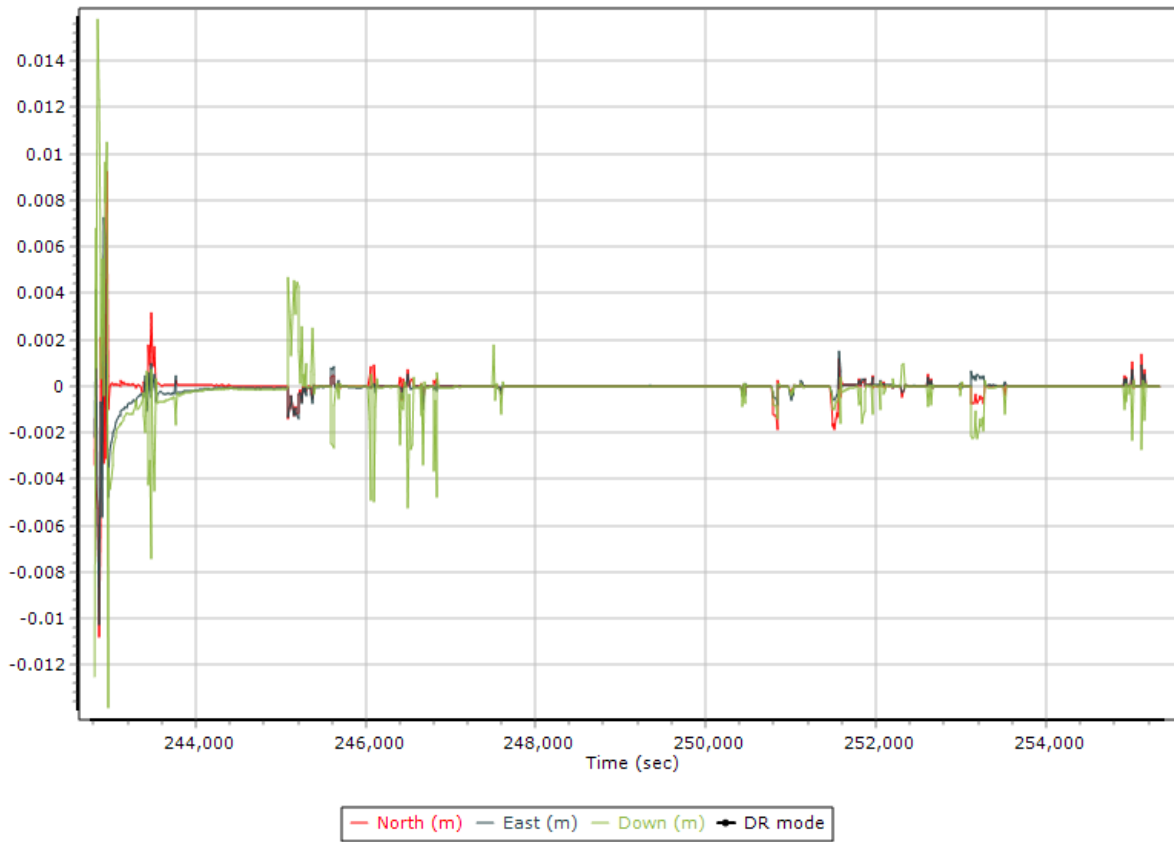
Z:

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: 240120.000
 End: 257176.000

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

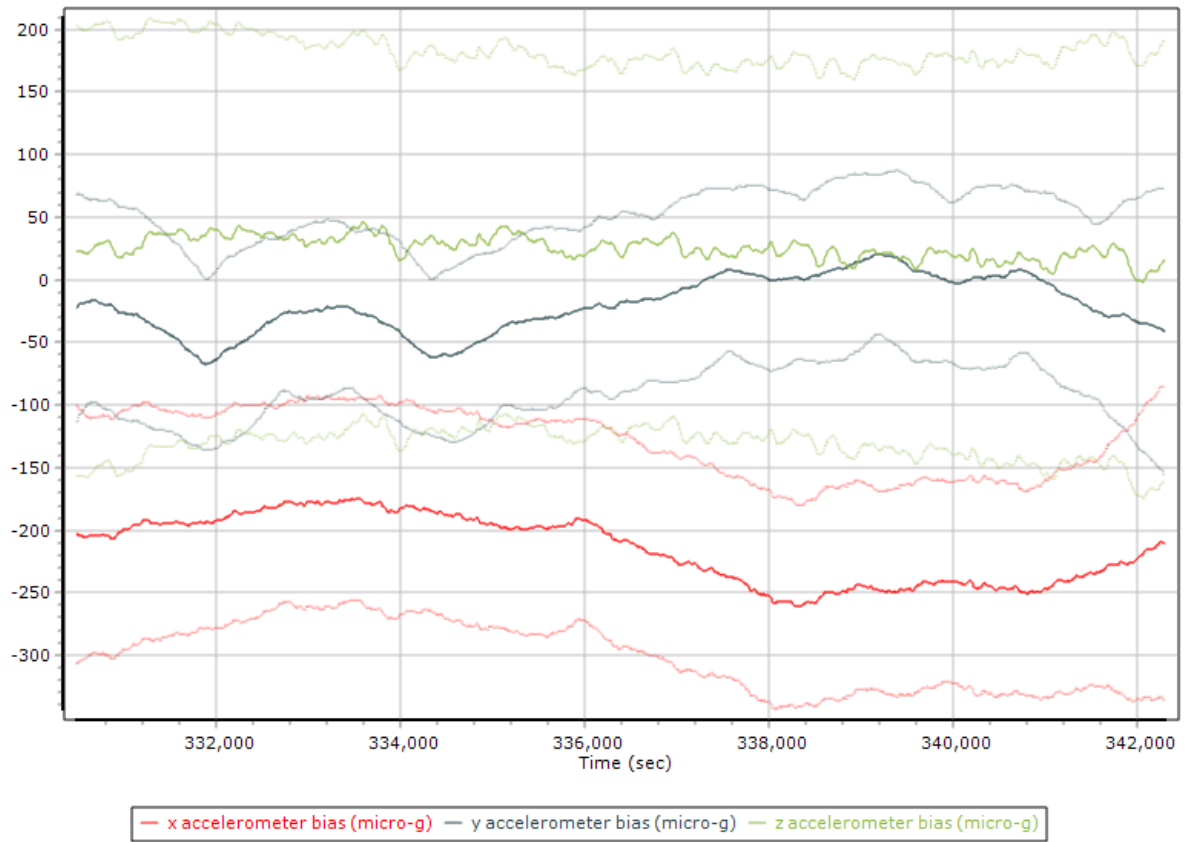
Processable Time Windows

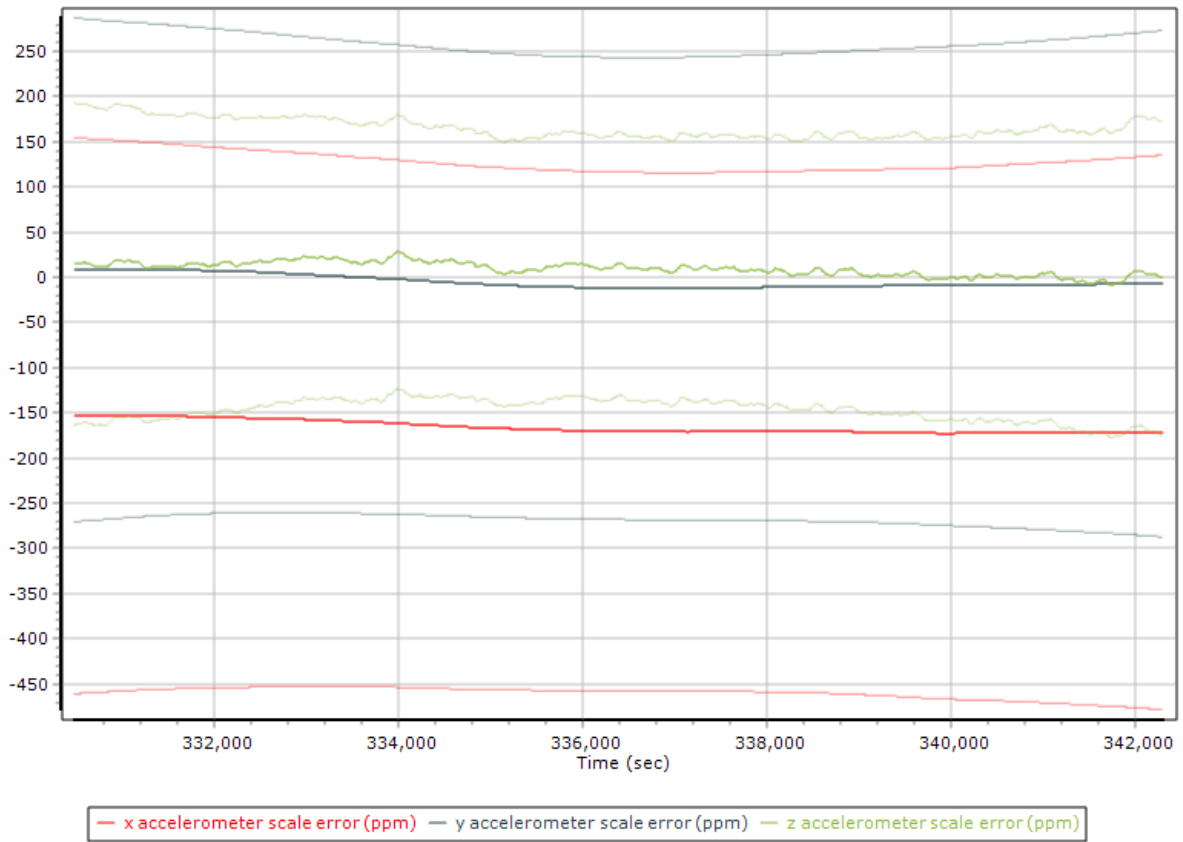
Start after launch Wait Time: 4.000 sec

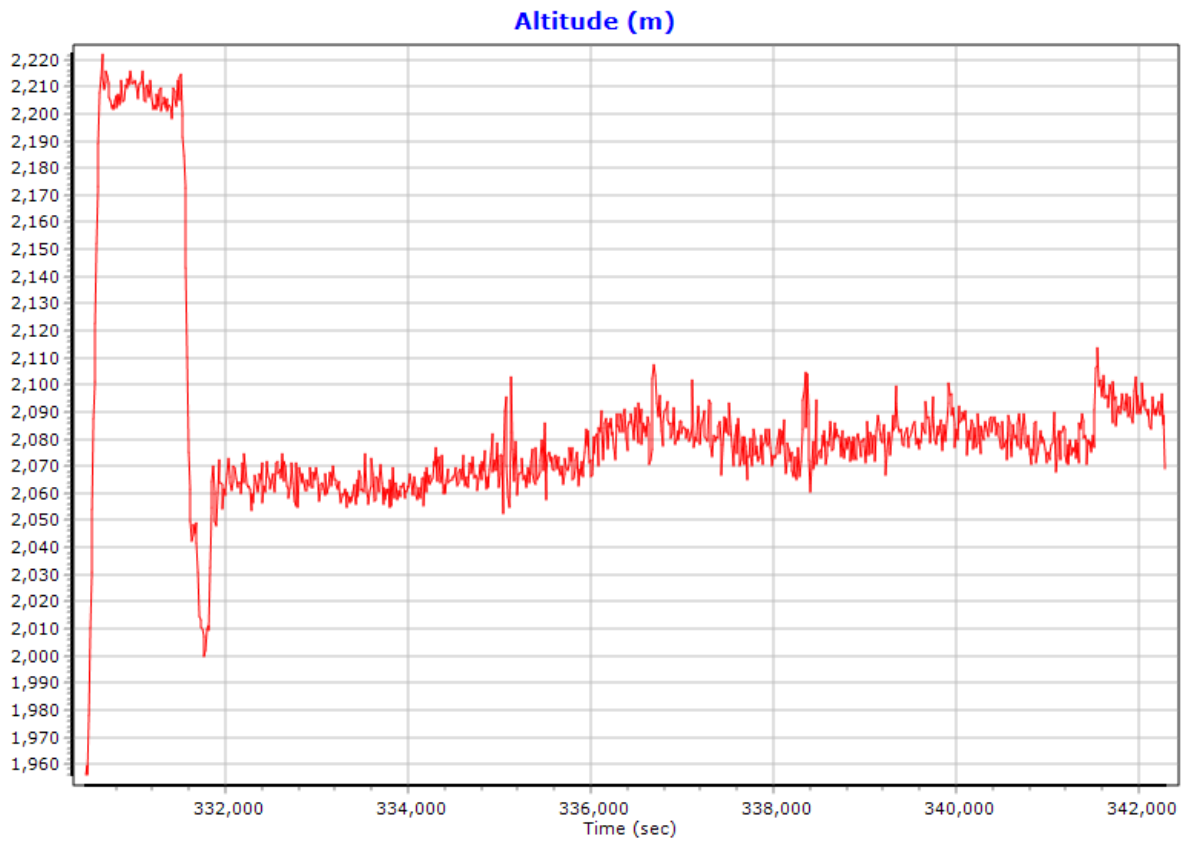
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	240120.000	257176.000	17056.000	End of file

OK Cancel

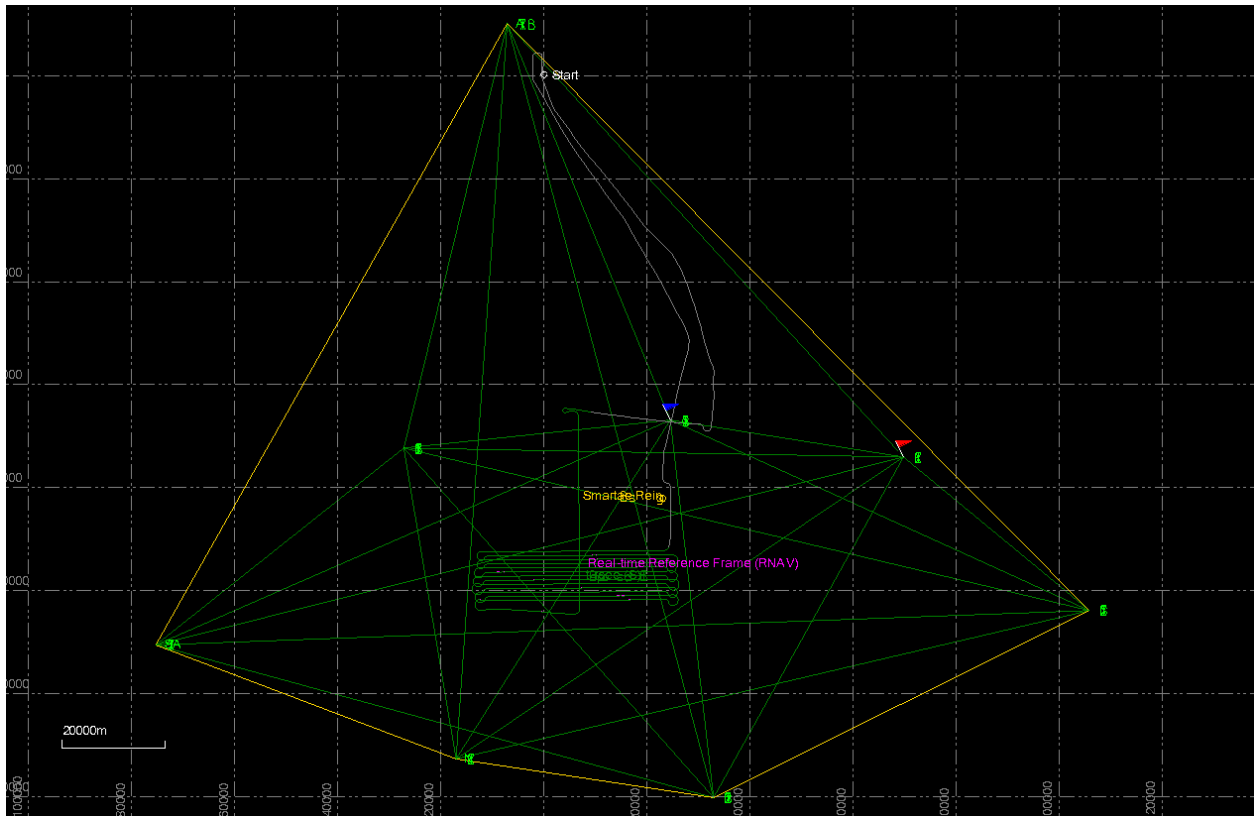
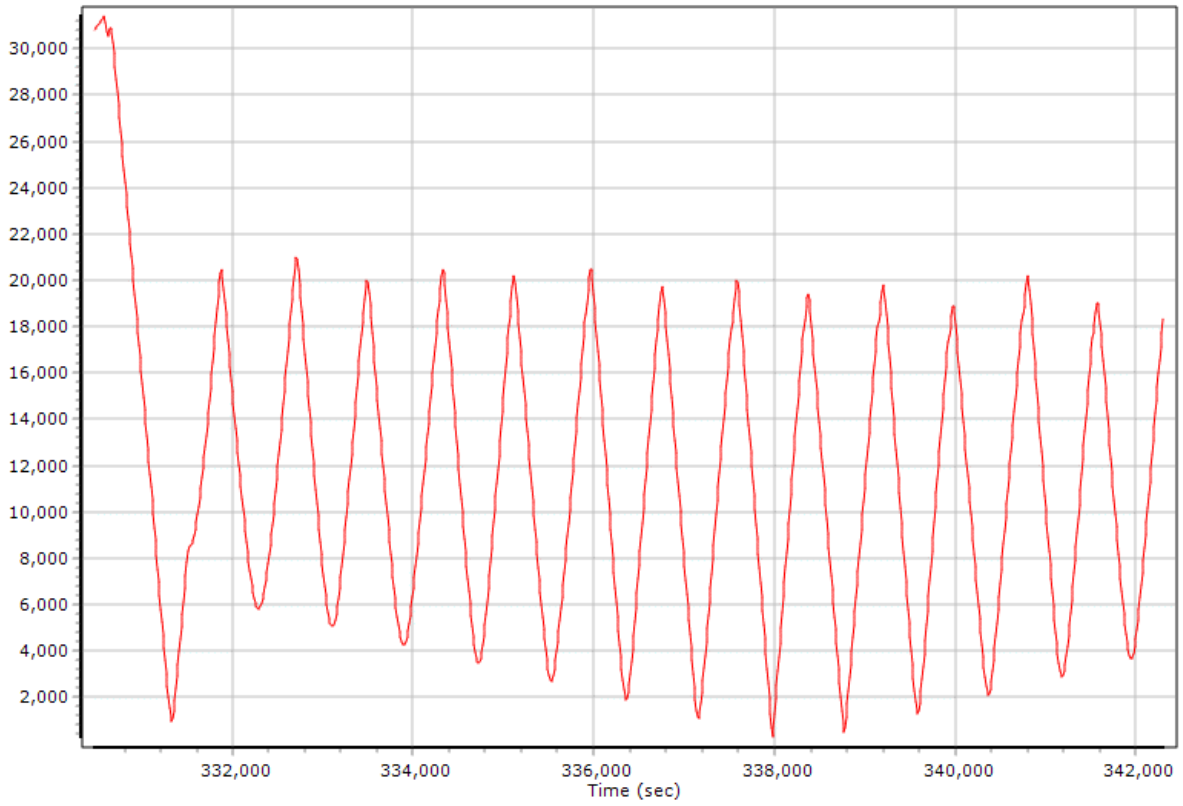
CAU18073A

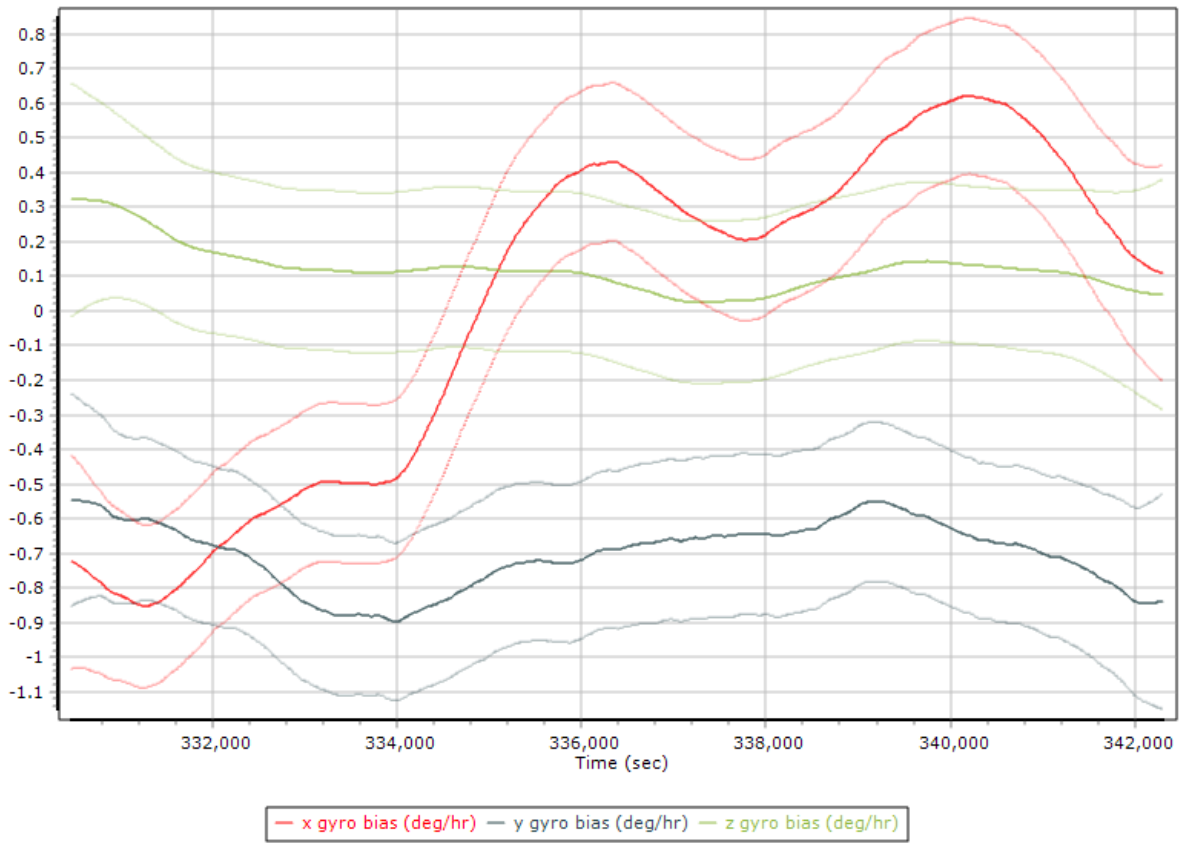


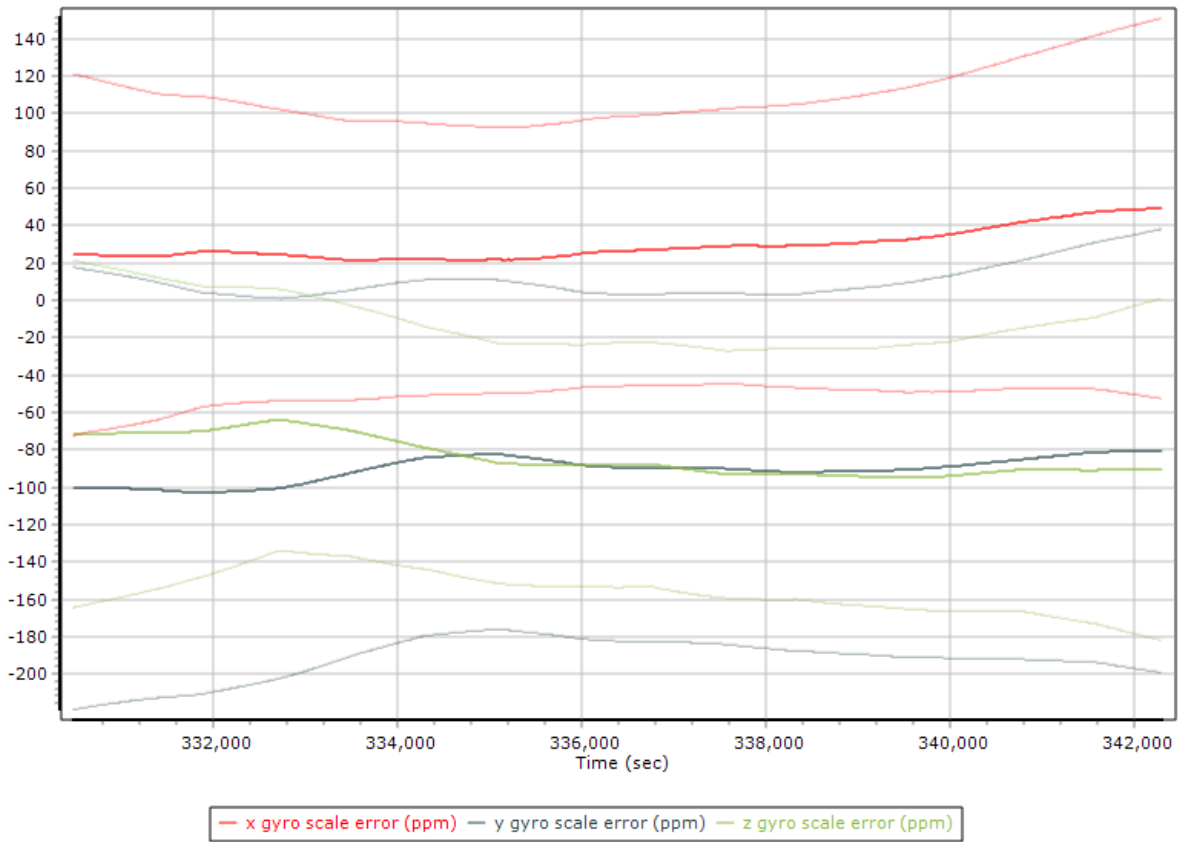




Baseline Length (m)







Project Settings ✕

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

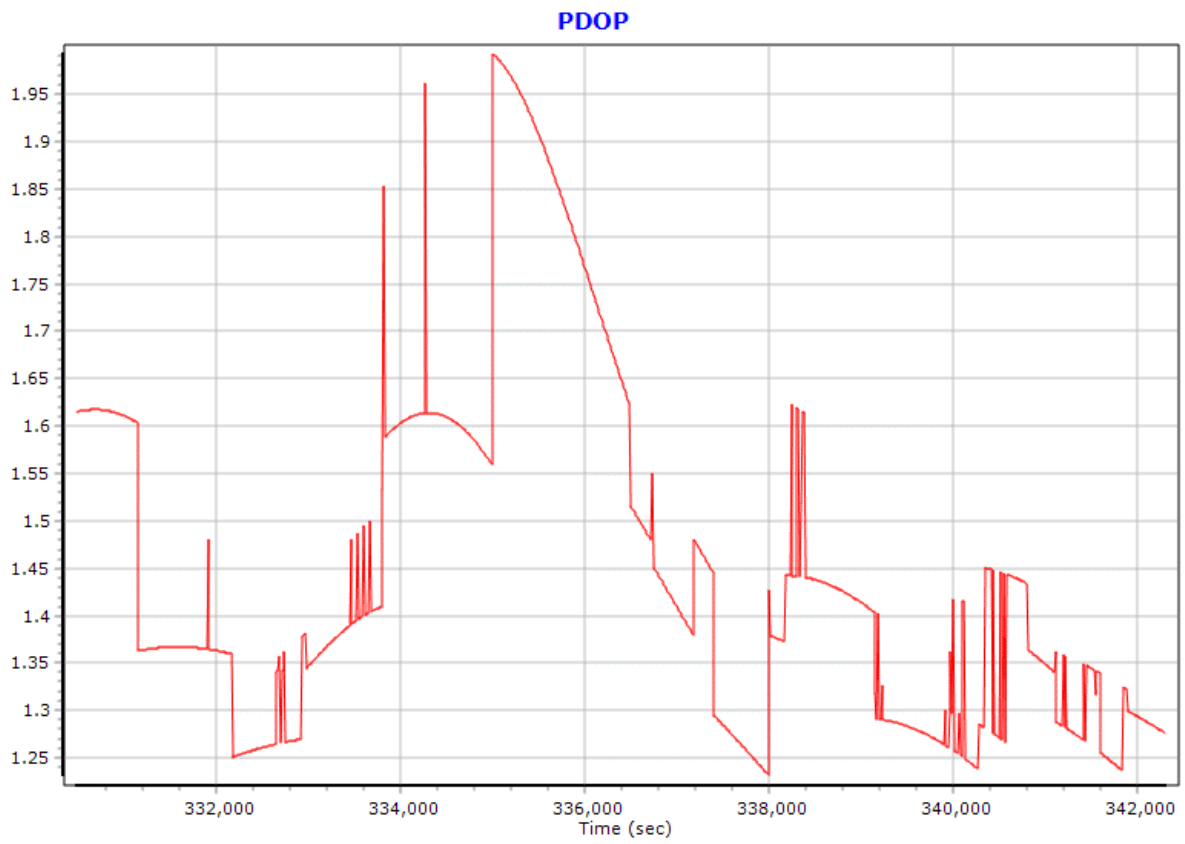
<3cm 10cm 50cm 1m 10m

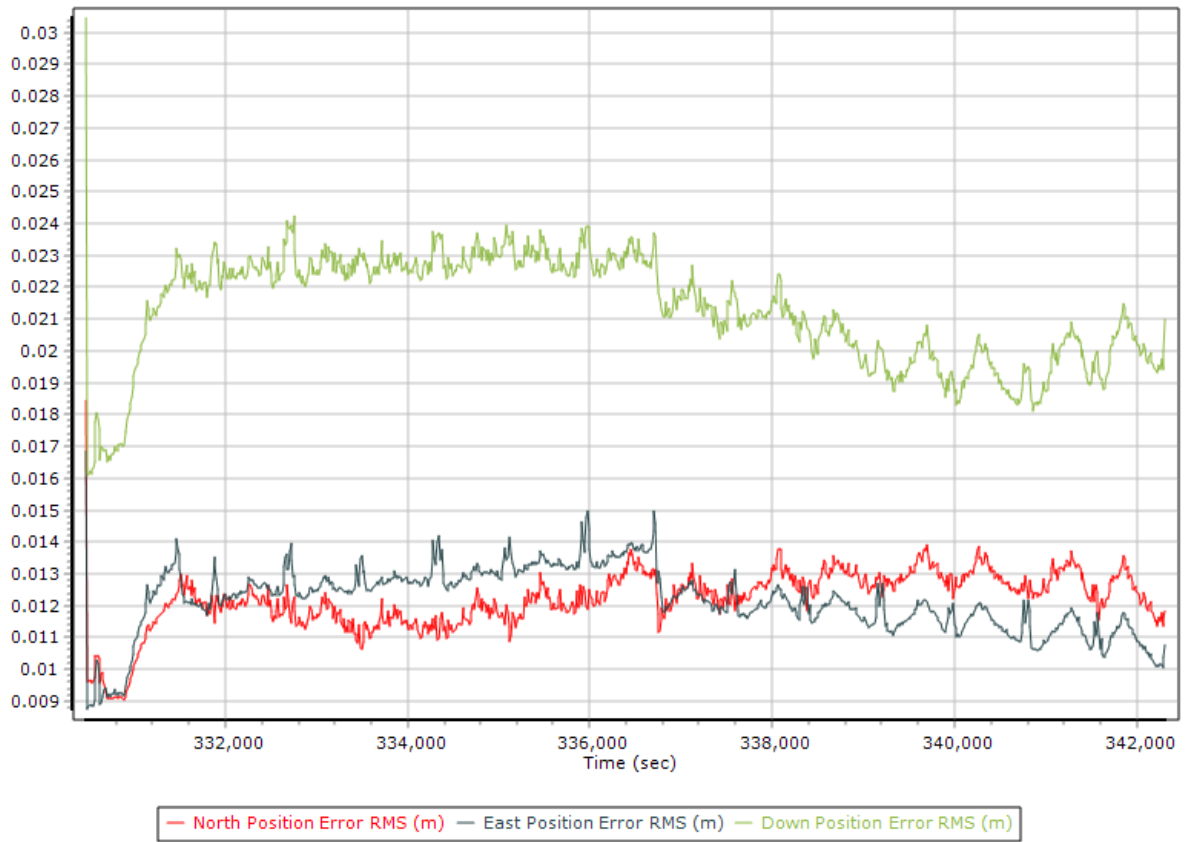
Aircraft to Reference Mounting Angles

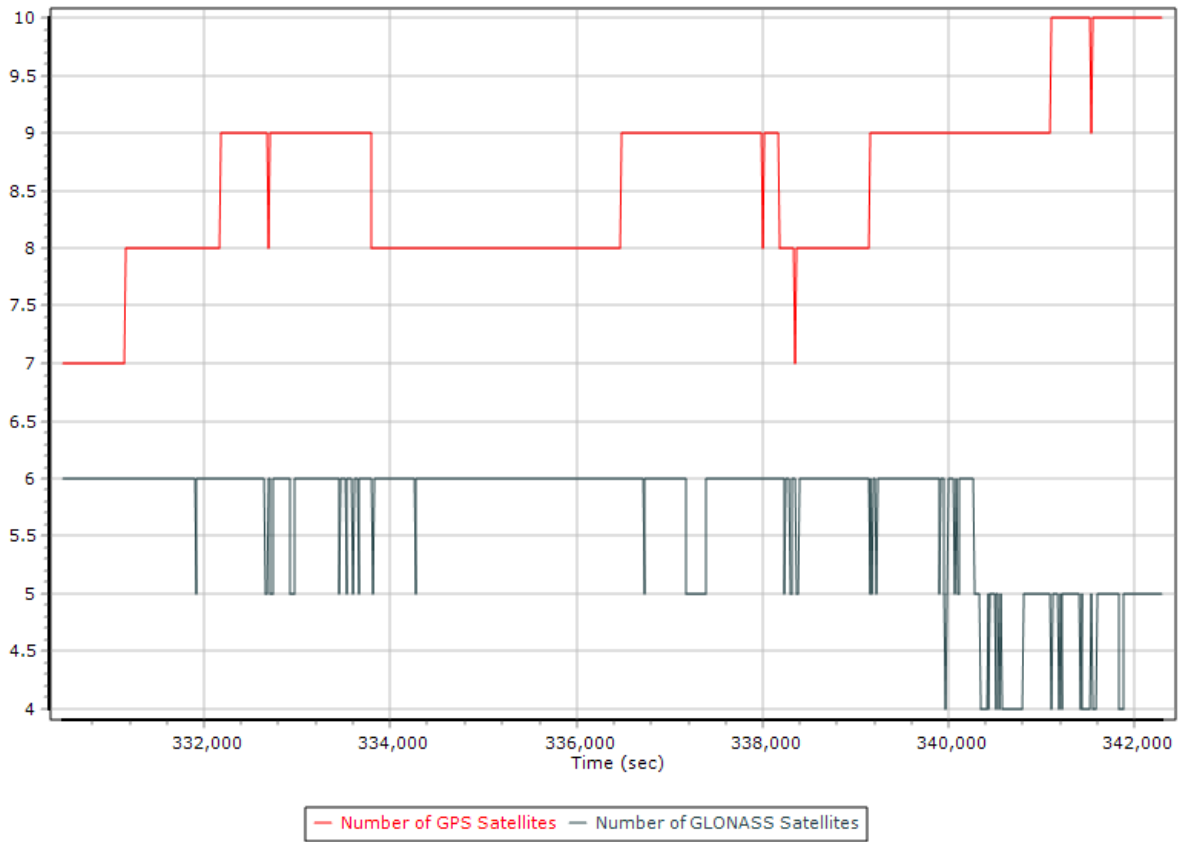
X:

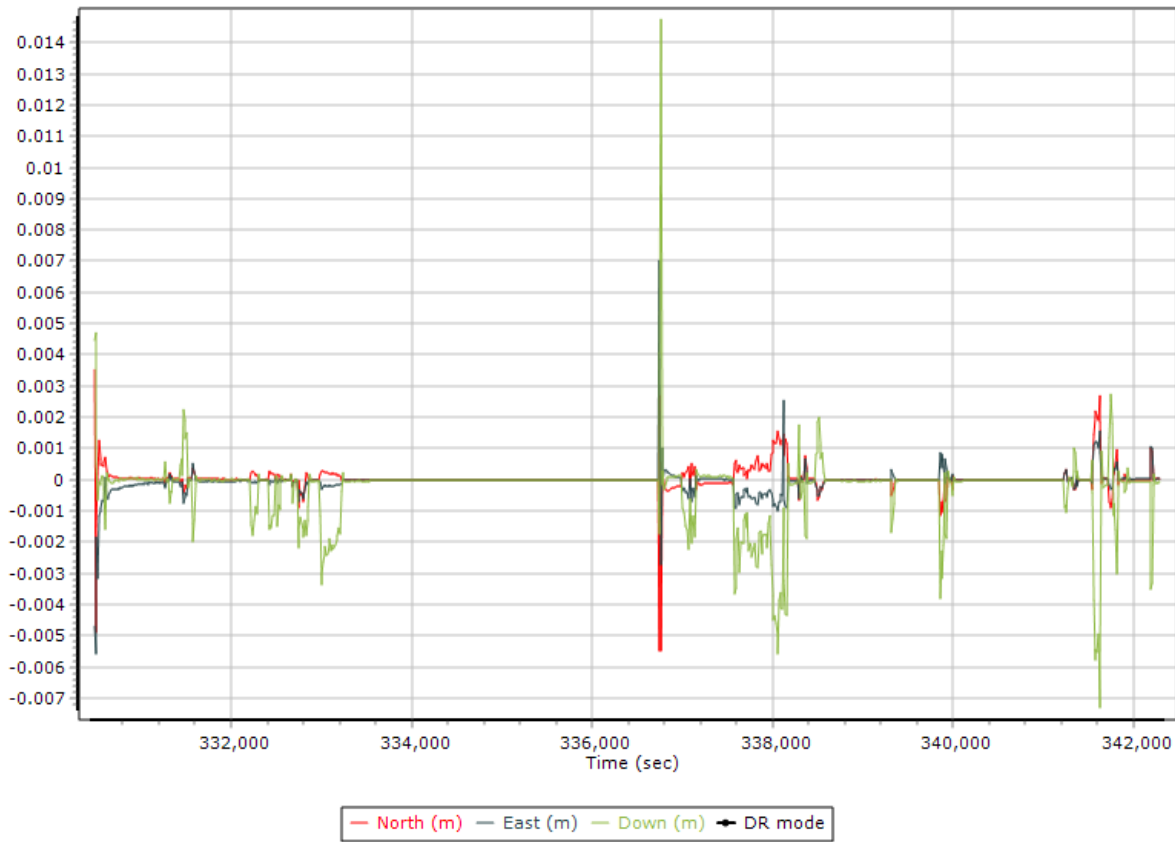
Y:

Z:









Project Settings [X]

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

Timing

Start: 327434.000
 End: 344266.000
 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

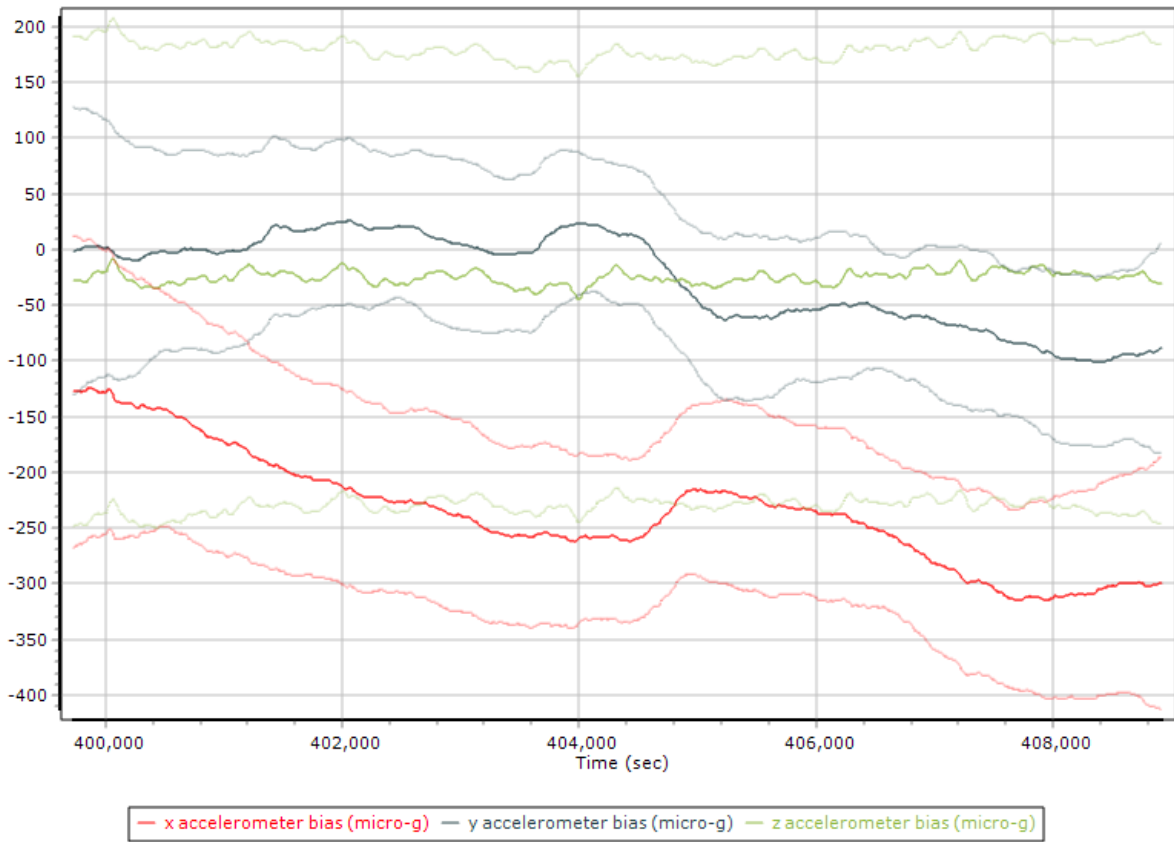
Processable Time Windows

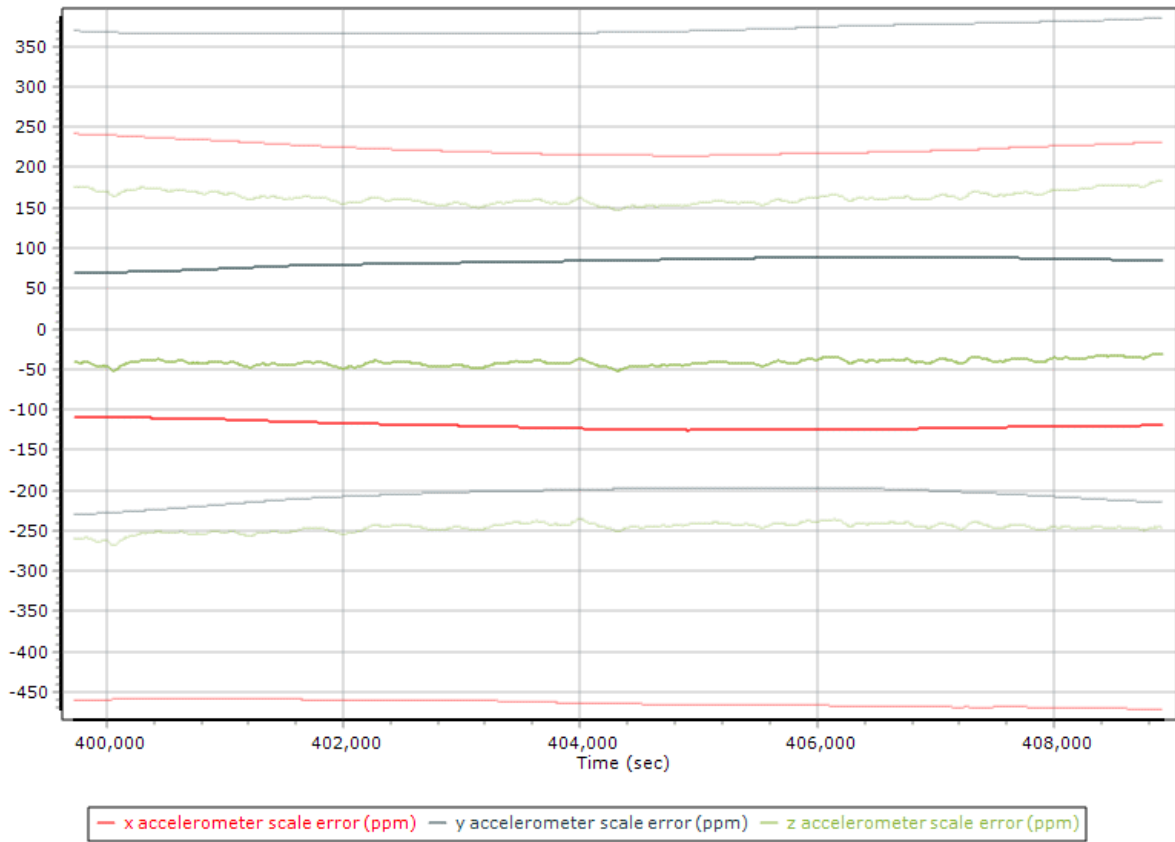
Start after launch Wait Time: 4.000 sec

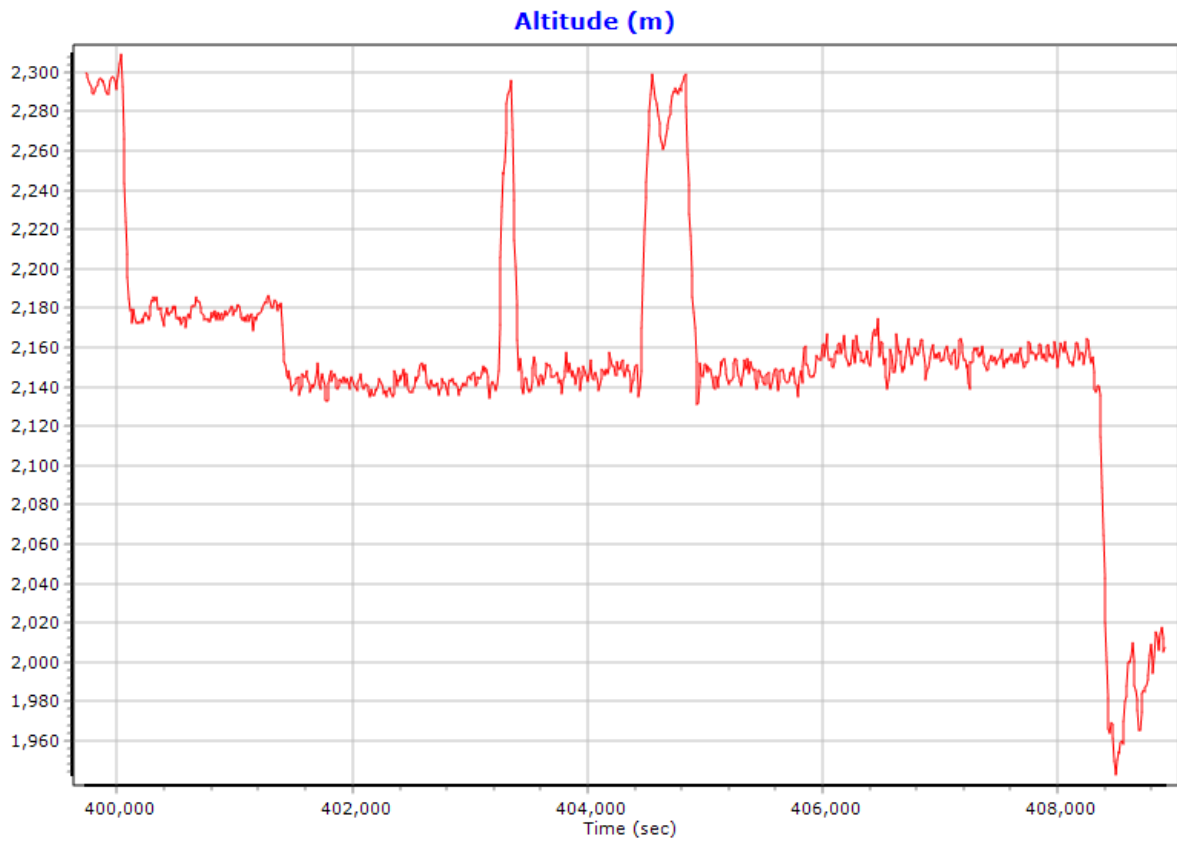
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	327434.000	344266.000	16832.000	End of file

OK Cancel

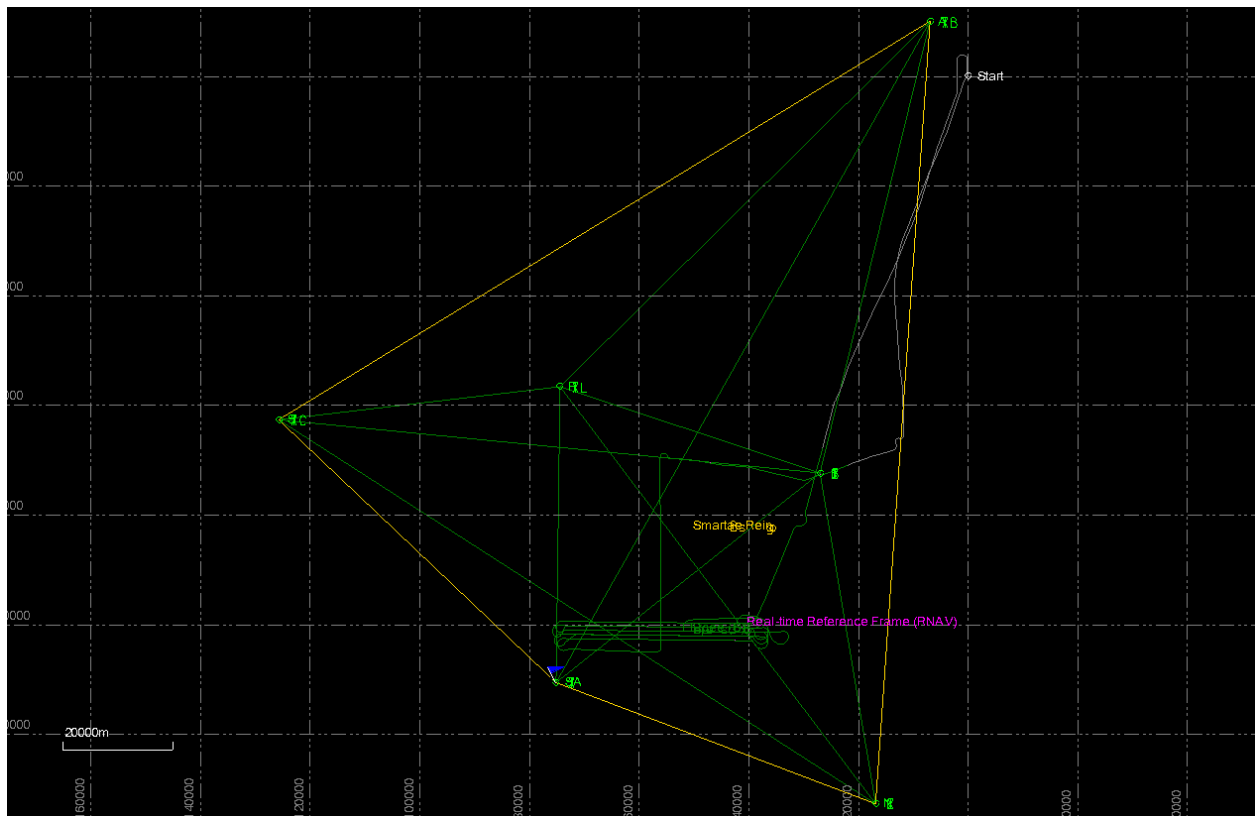
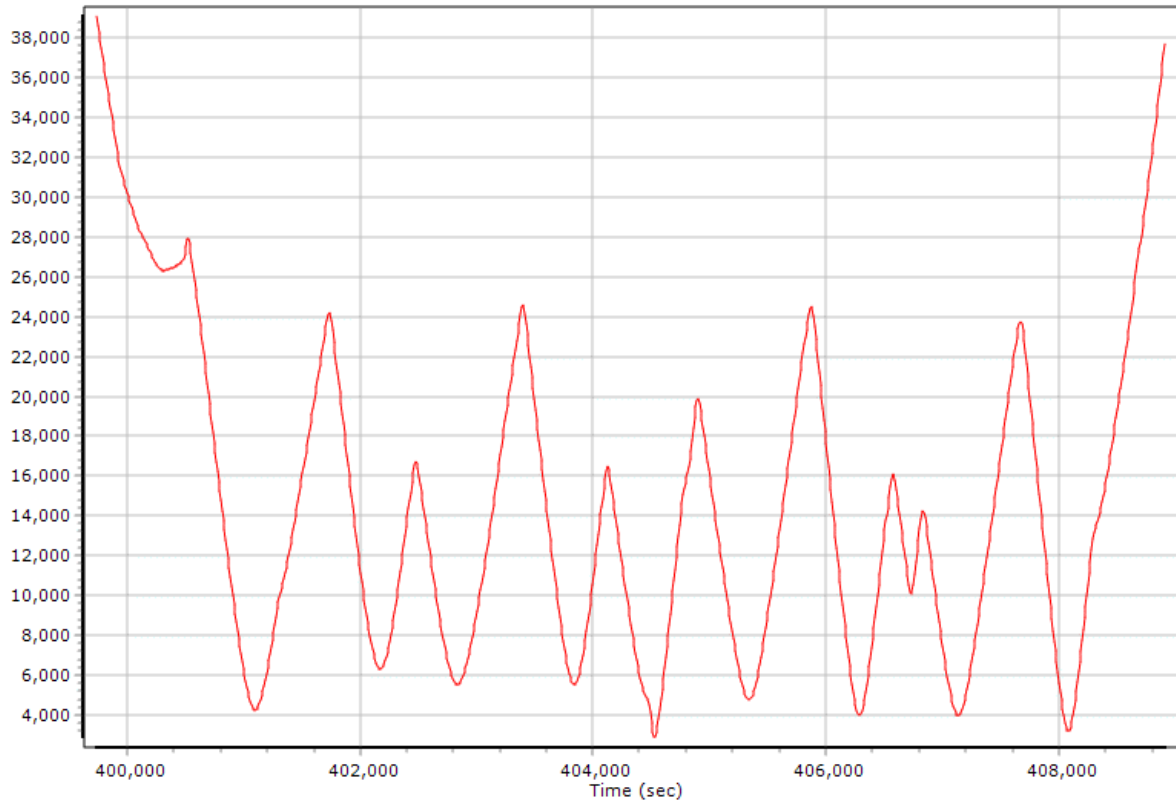
CAU18074A

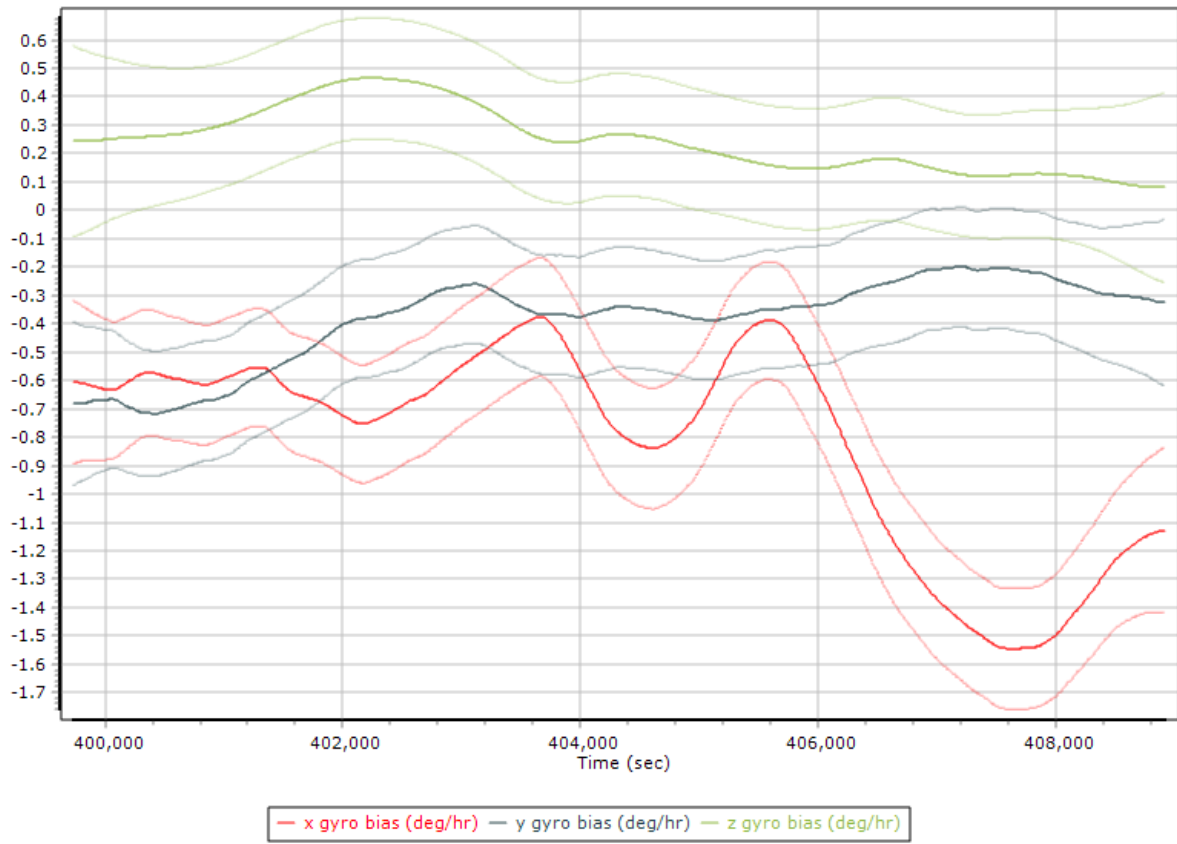


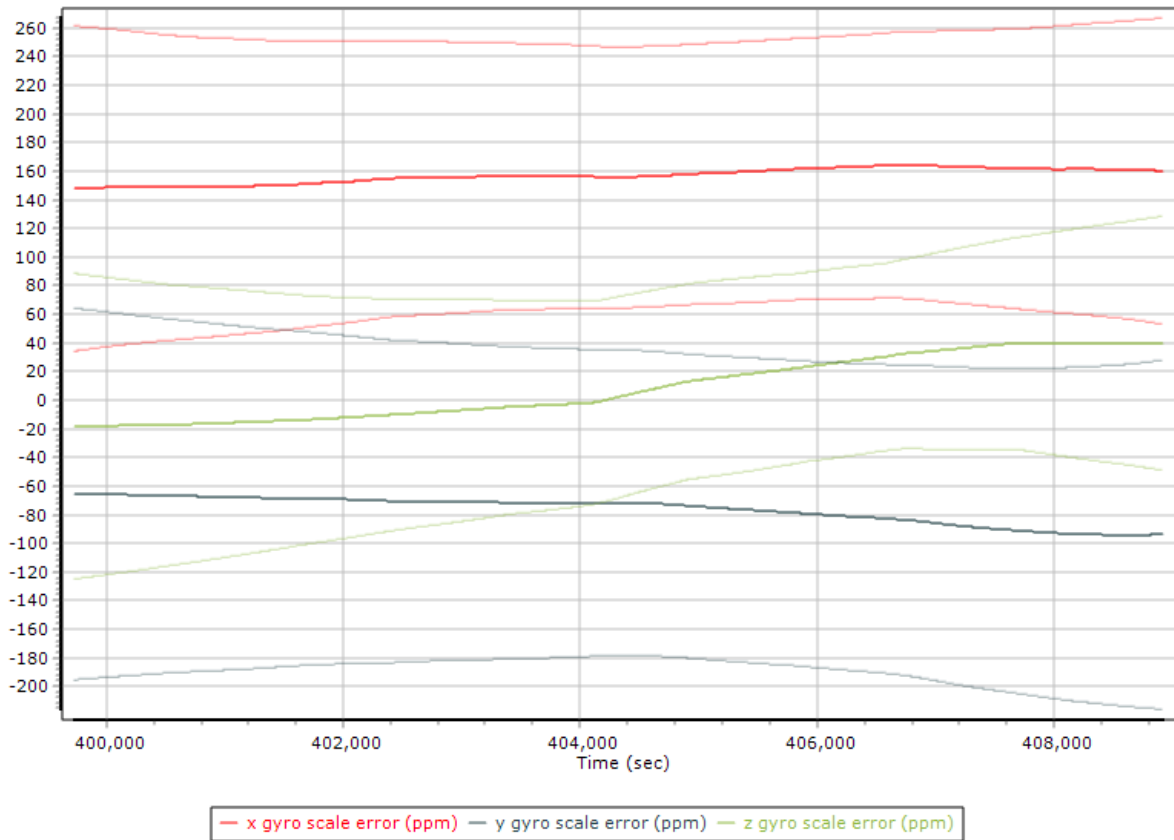




Baseline Length (m)







Project Settings [X]

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

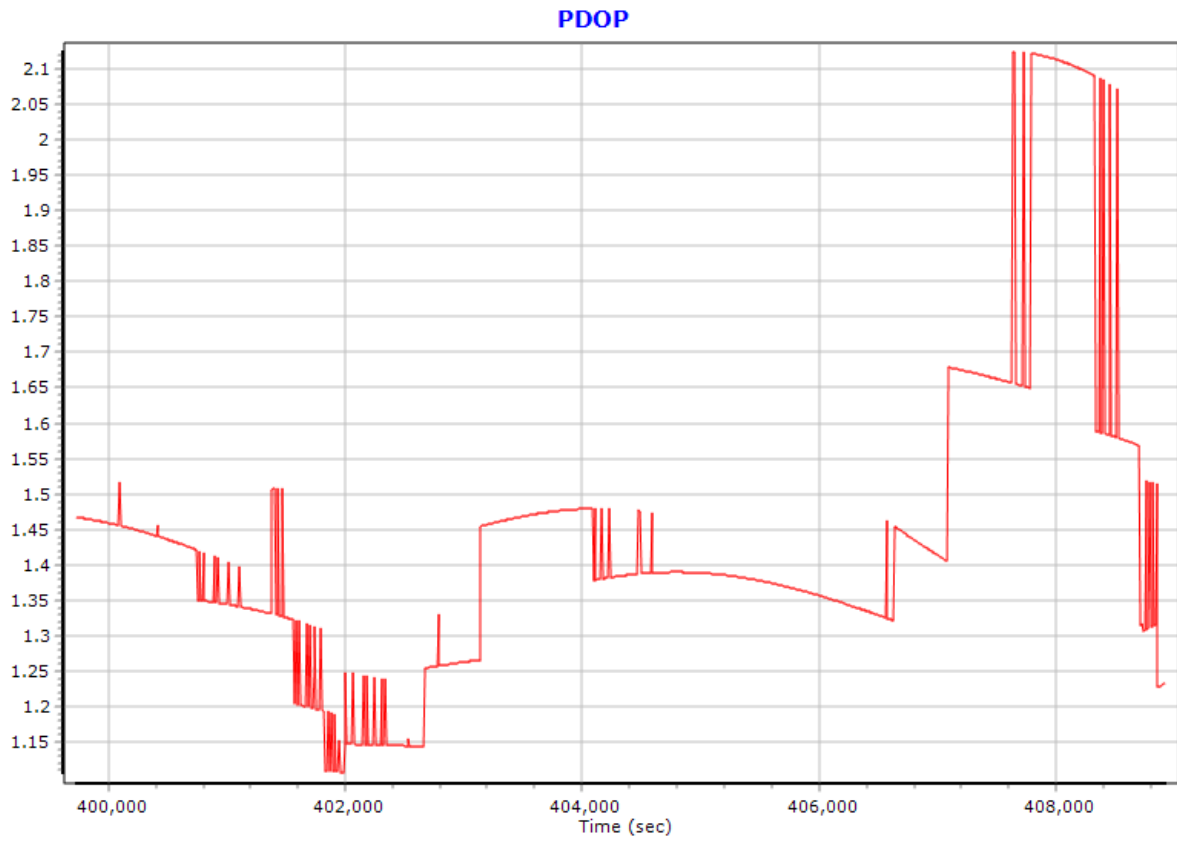
Aircraft to Reference Mounting Angles

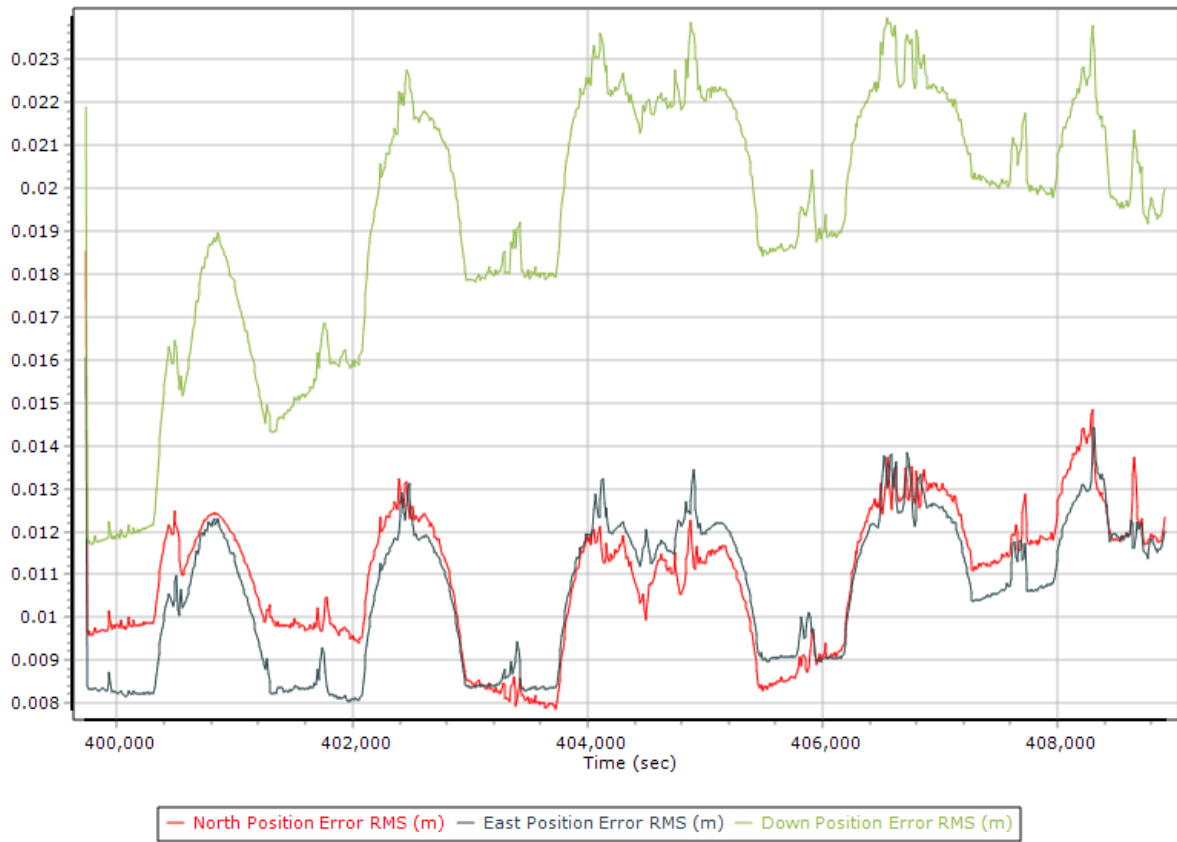
X:

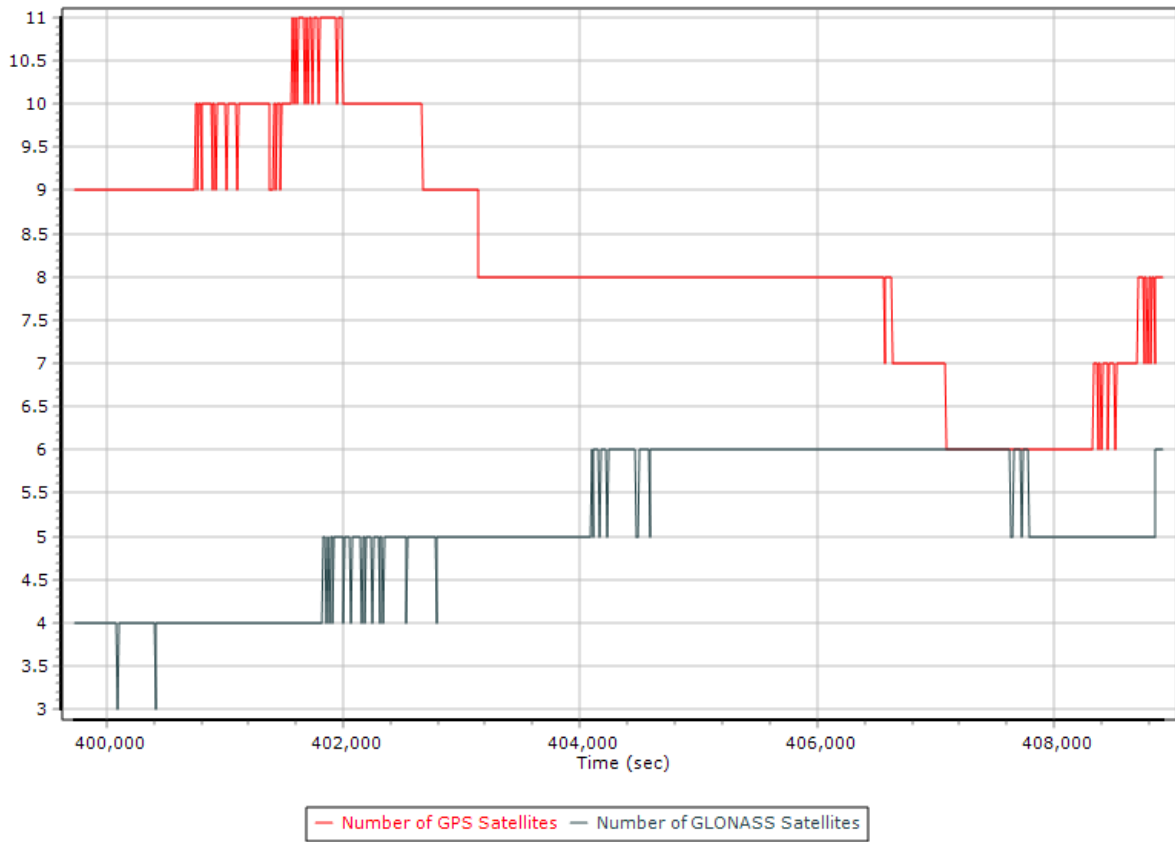
Y:

Z:

OK Cancel









Project Settings

- 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: 396970.000
 End: 410316.000

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

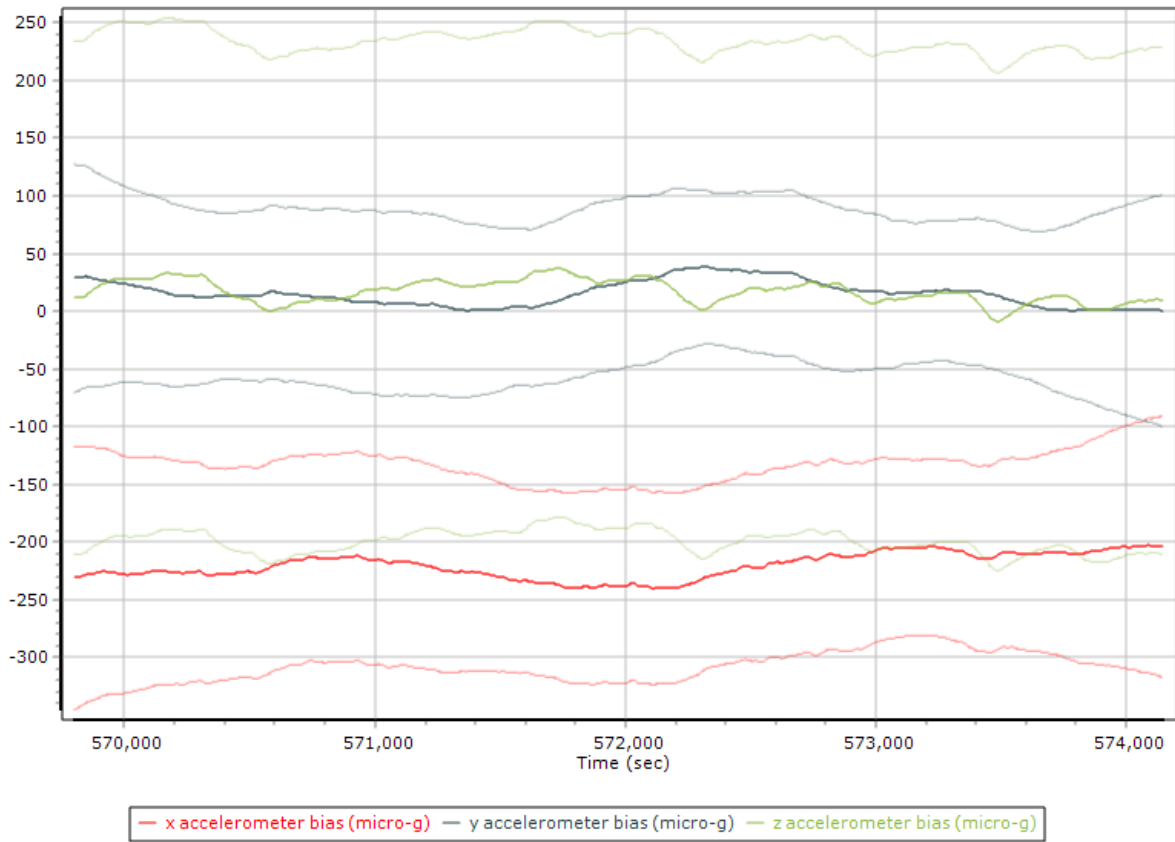
Processable Time Windows

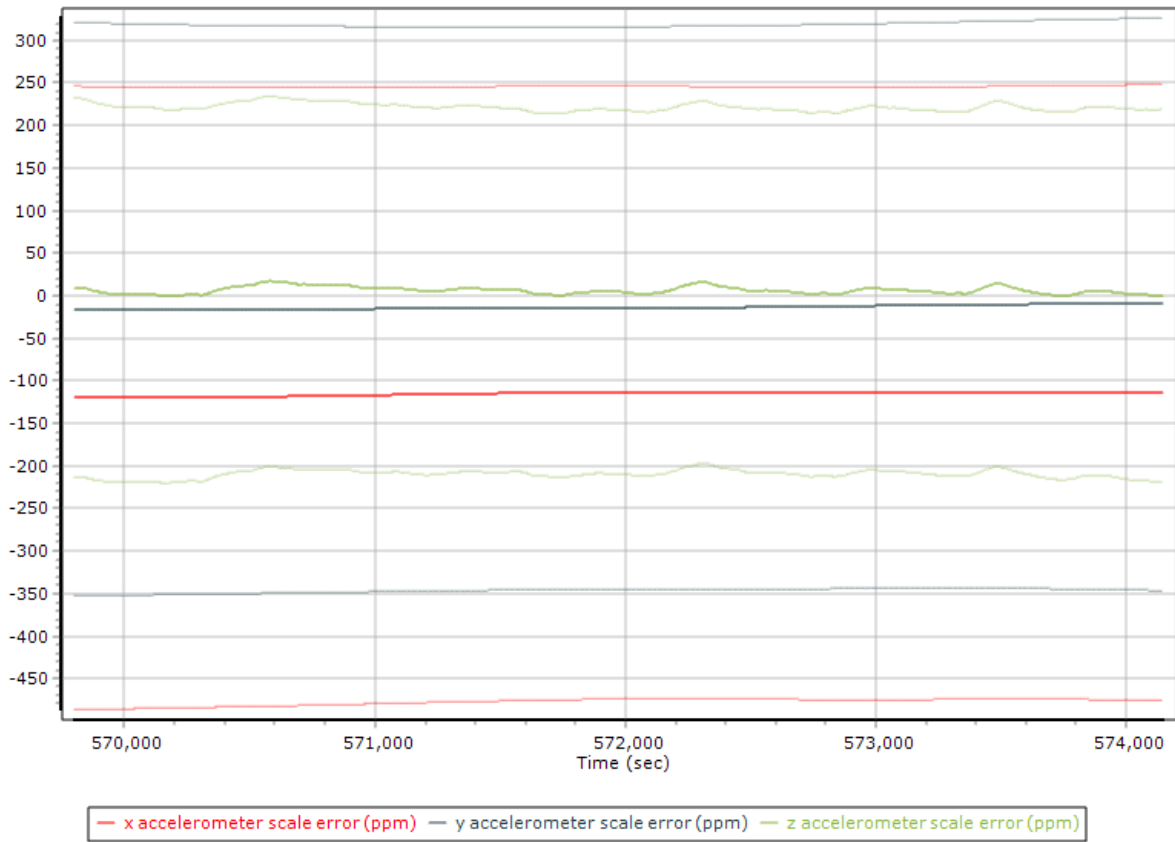
Start after launch Wait Time: 4.000 sec

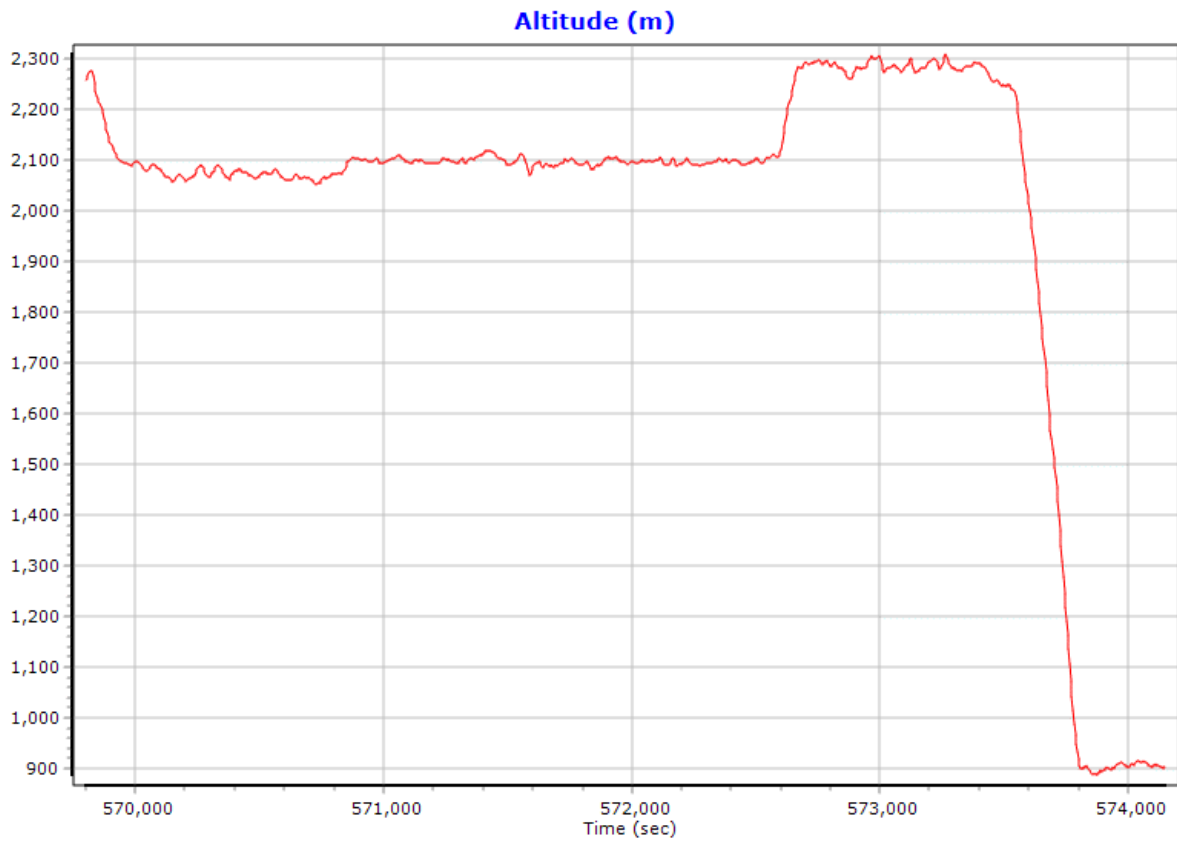
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	396970.000	410316.000	13346.000	End of file

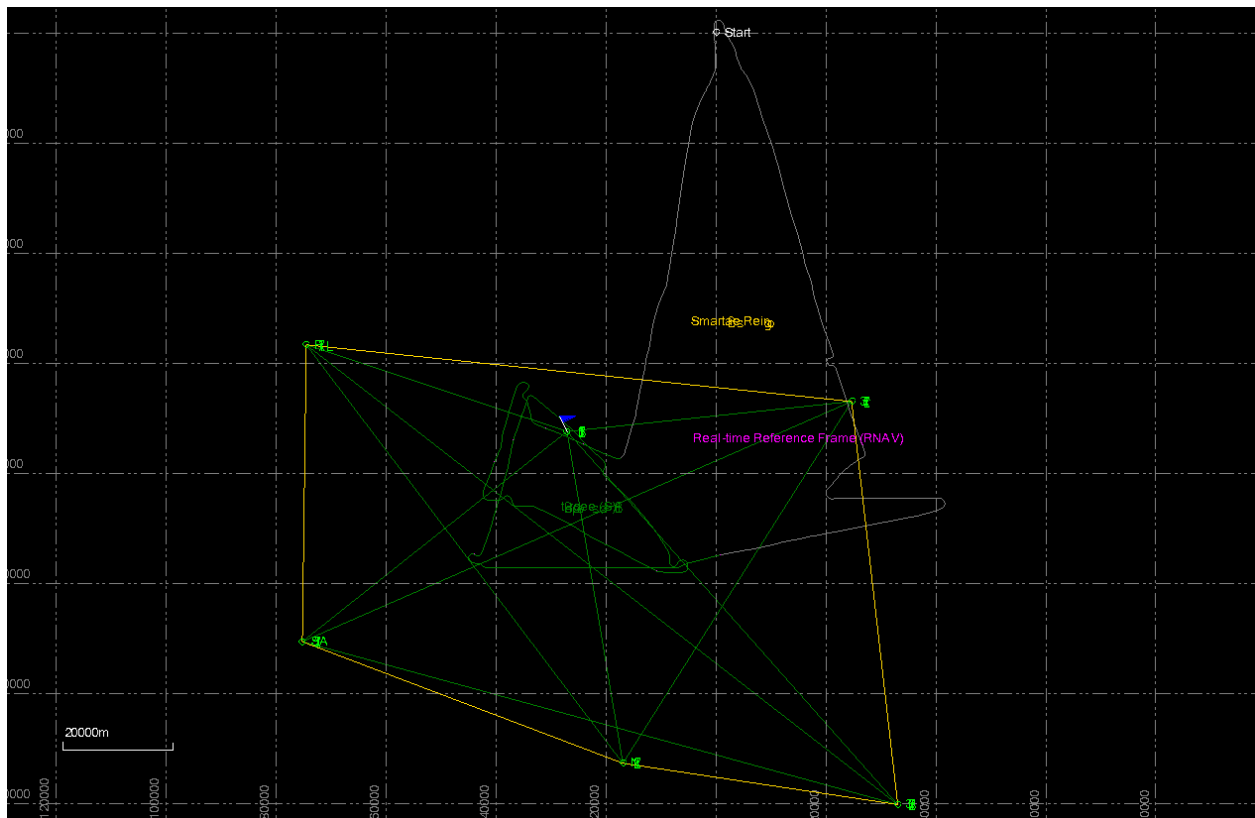
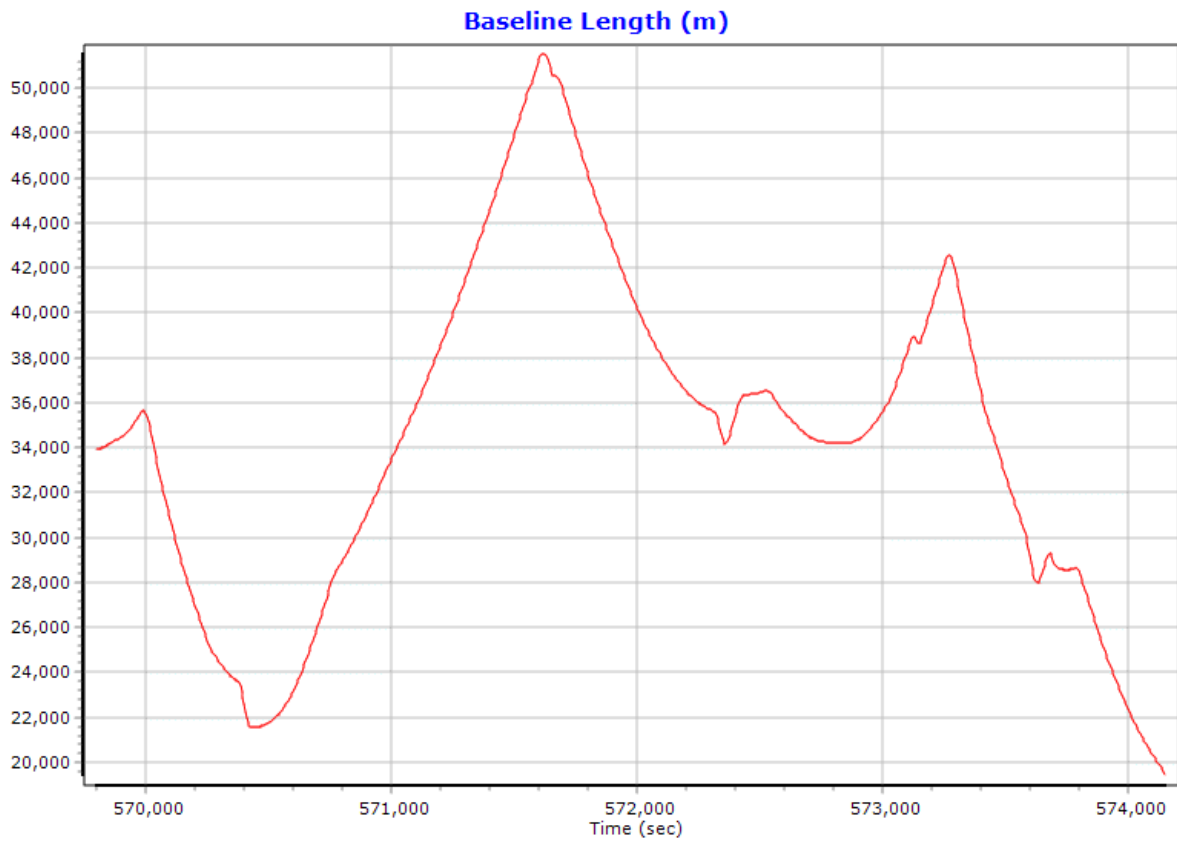
OK Cancel

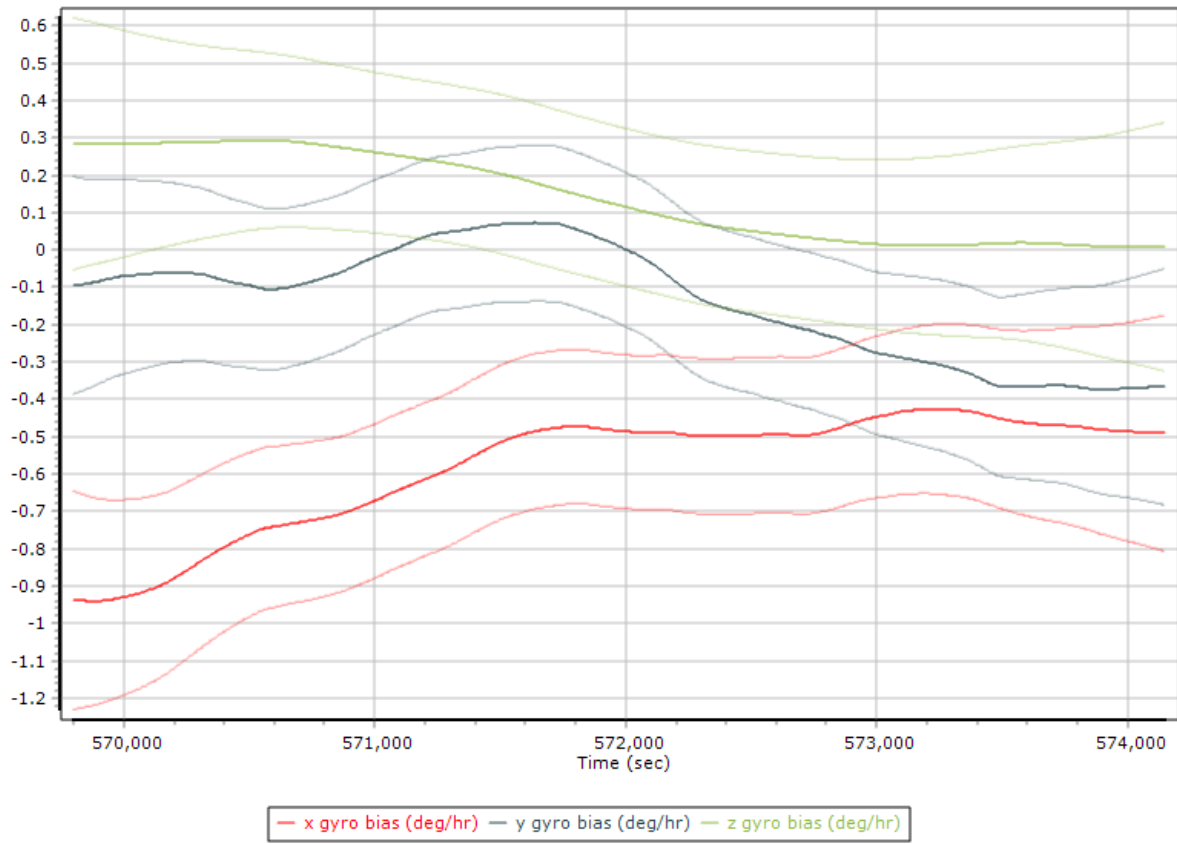
CAU18076A

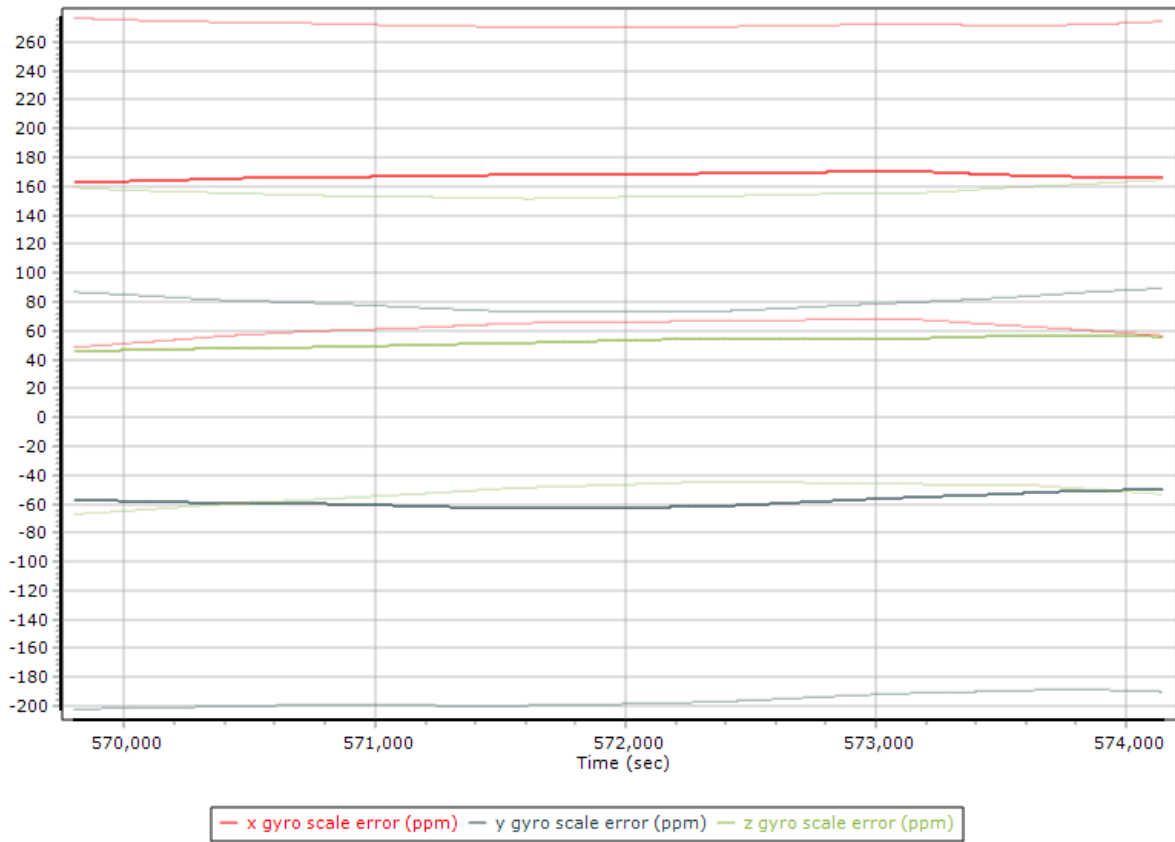












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

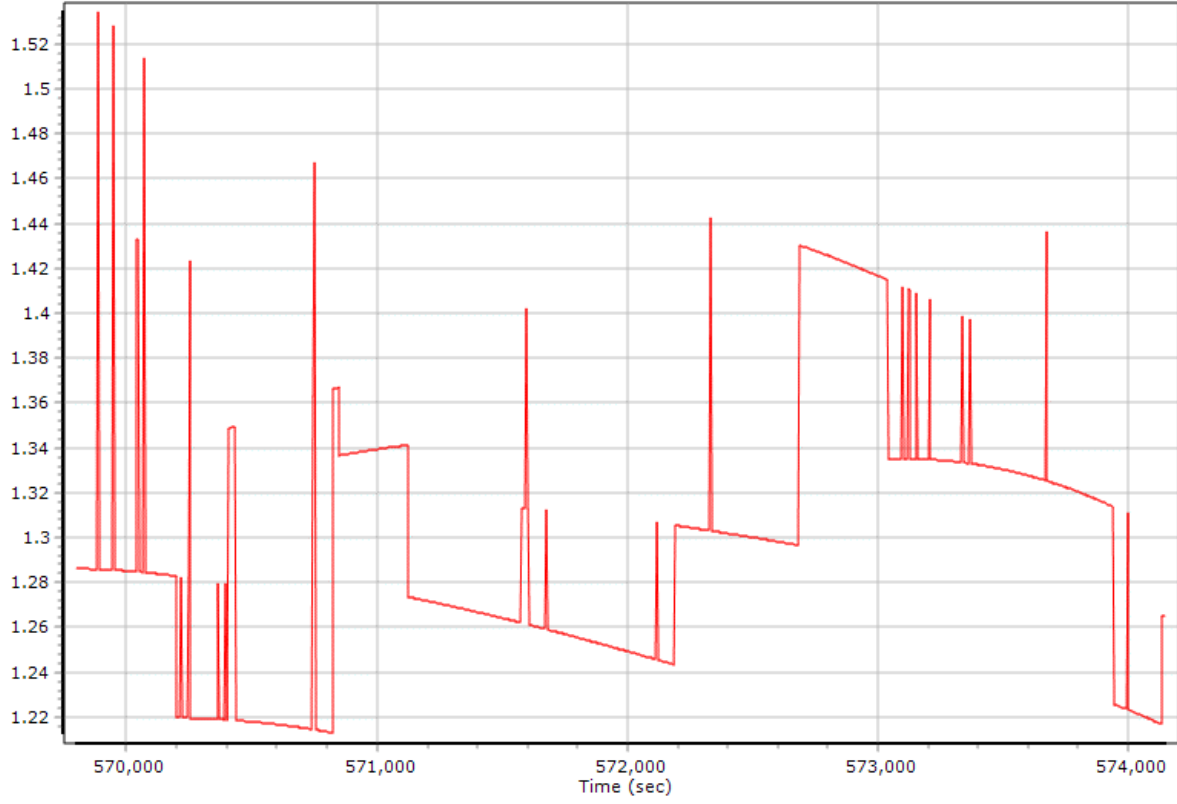
Aircraft to Reference Mounting Angles

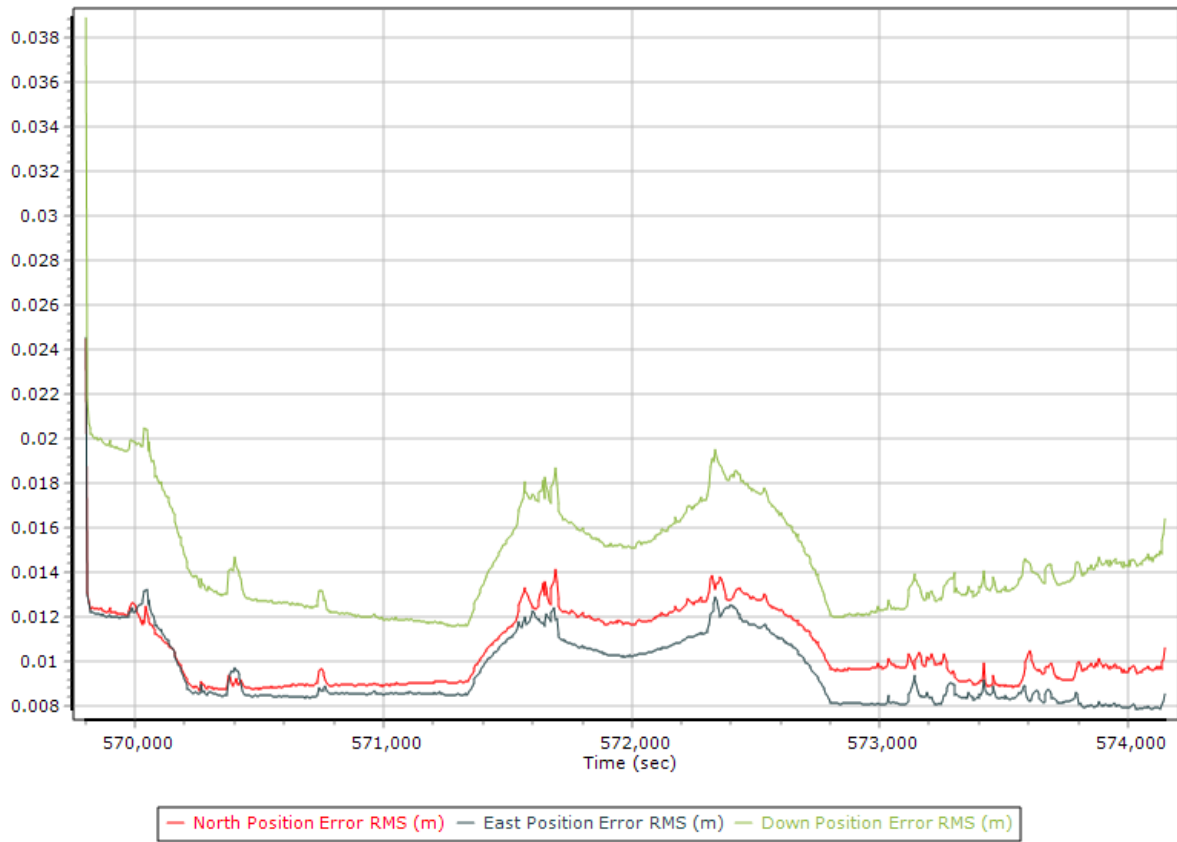
X:

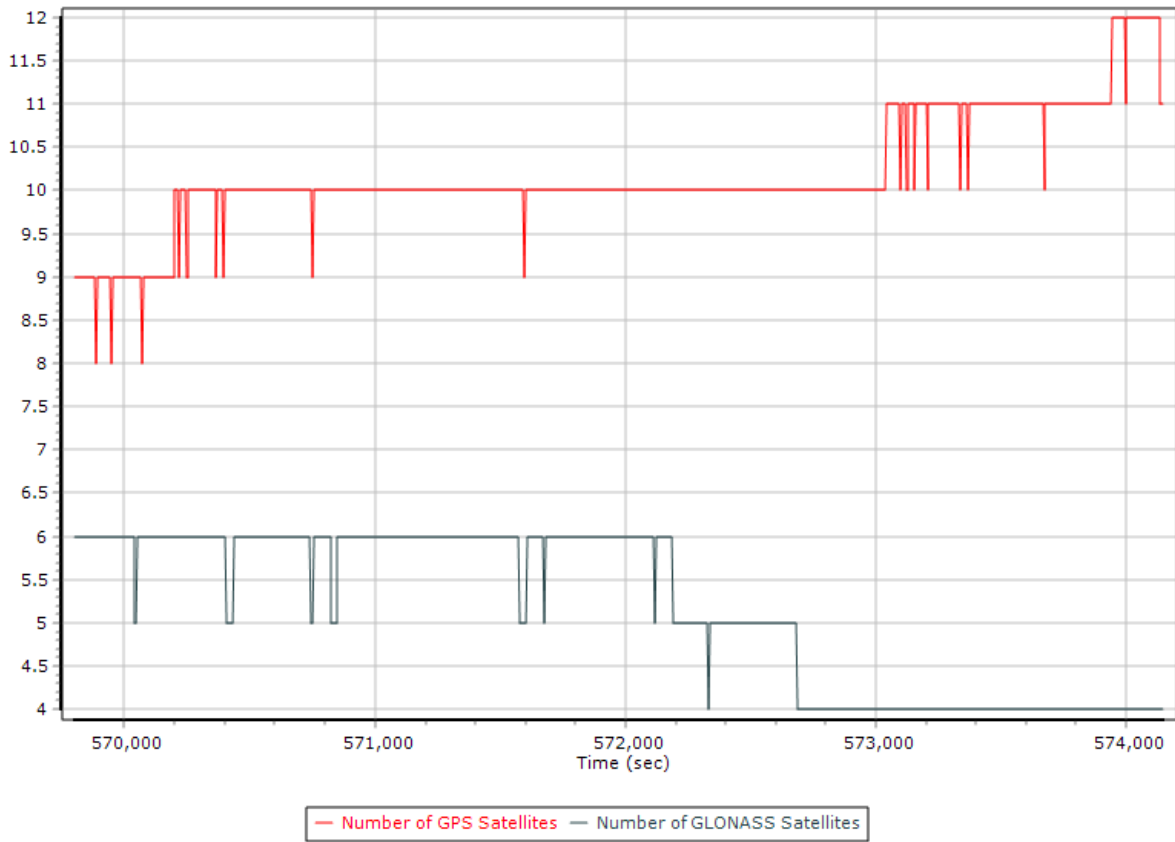
Y:

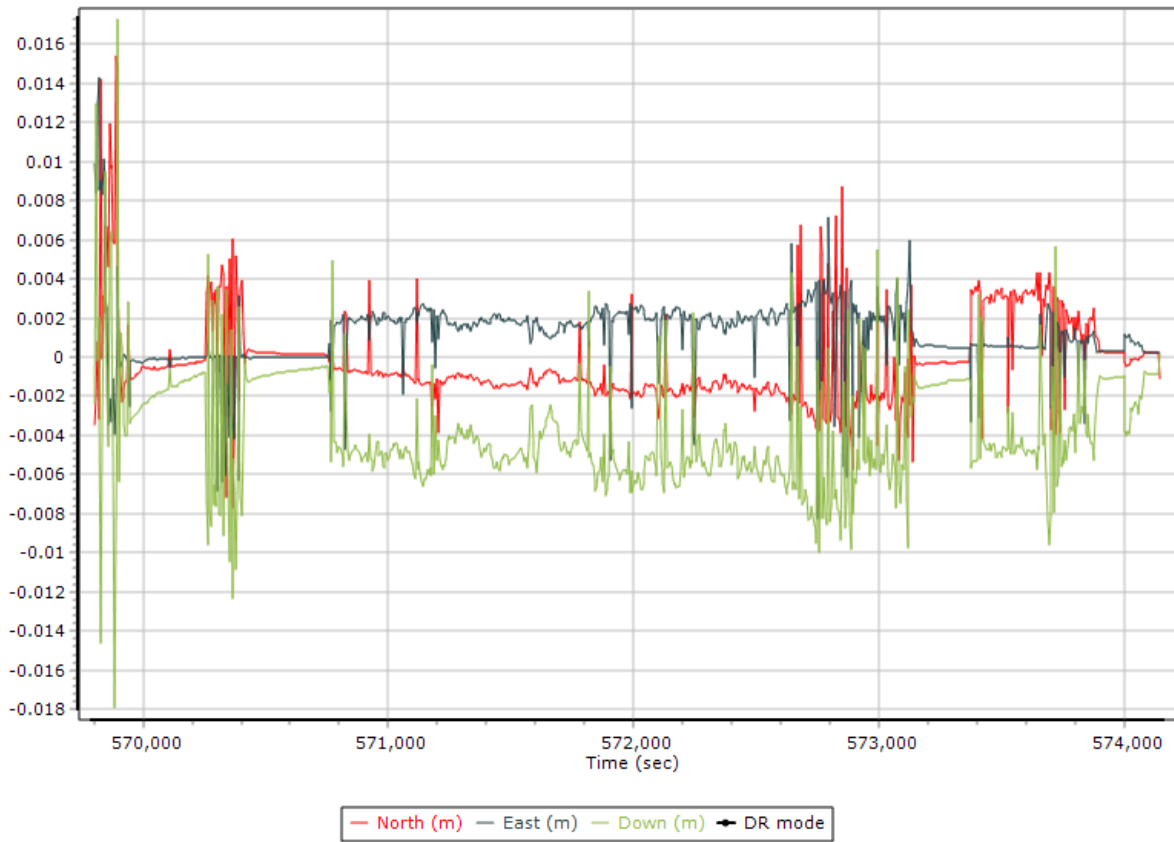
Z:

PDOP









Project Settings

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- Rover Import
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- GNSS-Inertial Processor
 - Timing
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 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LIDAR
- SAR

Timing

Start: 565413.000
End: 575678.000

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

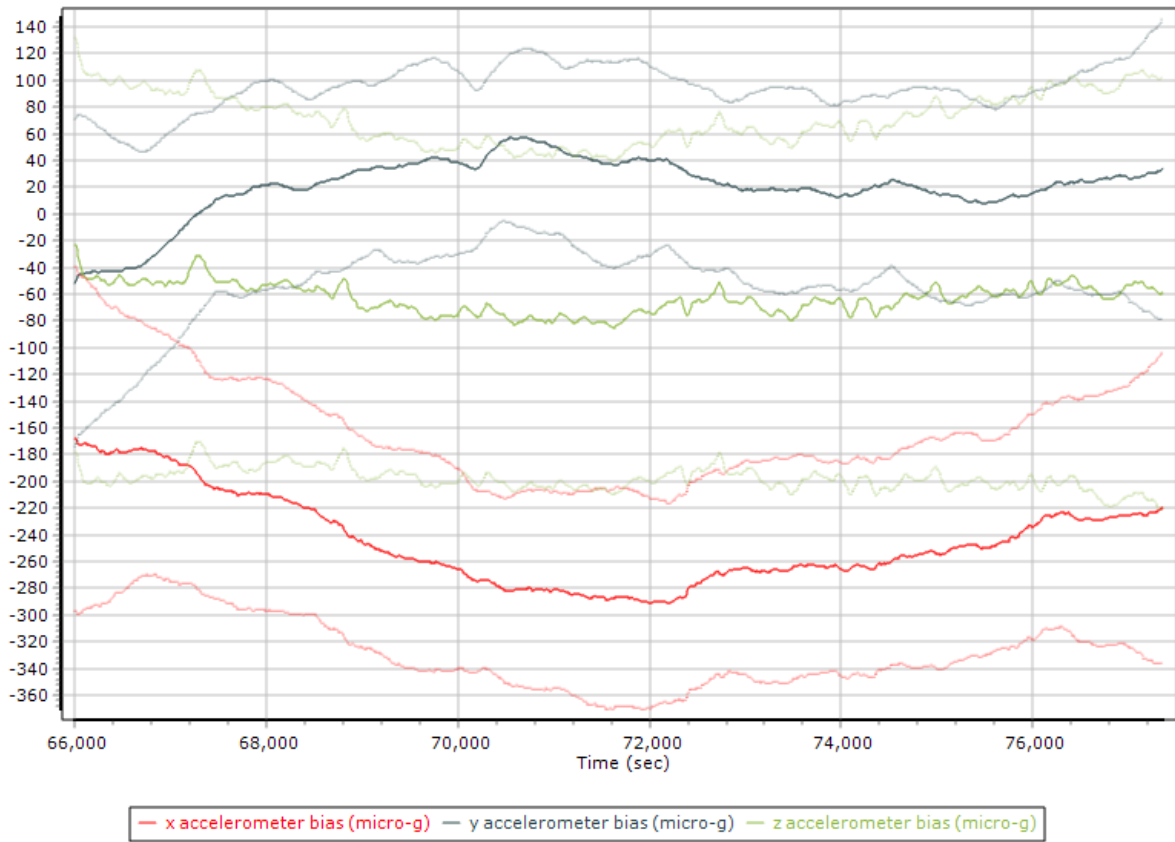
Processable Time Windows

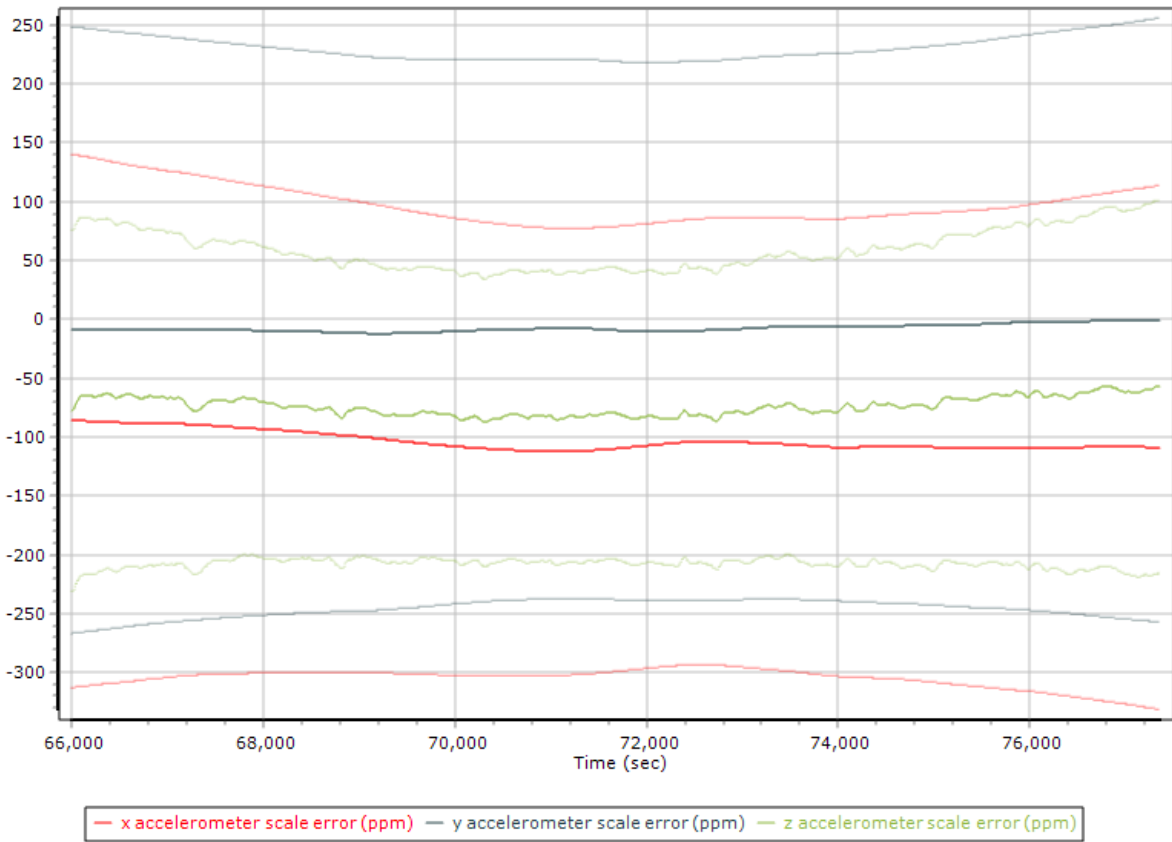
Start after launch Wait Time: 4.000 sec

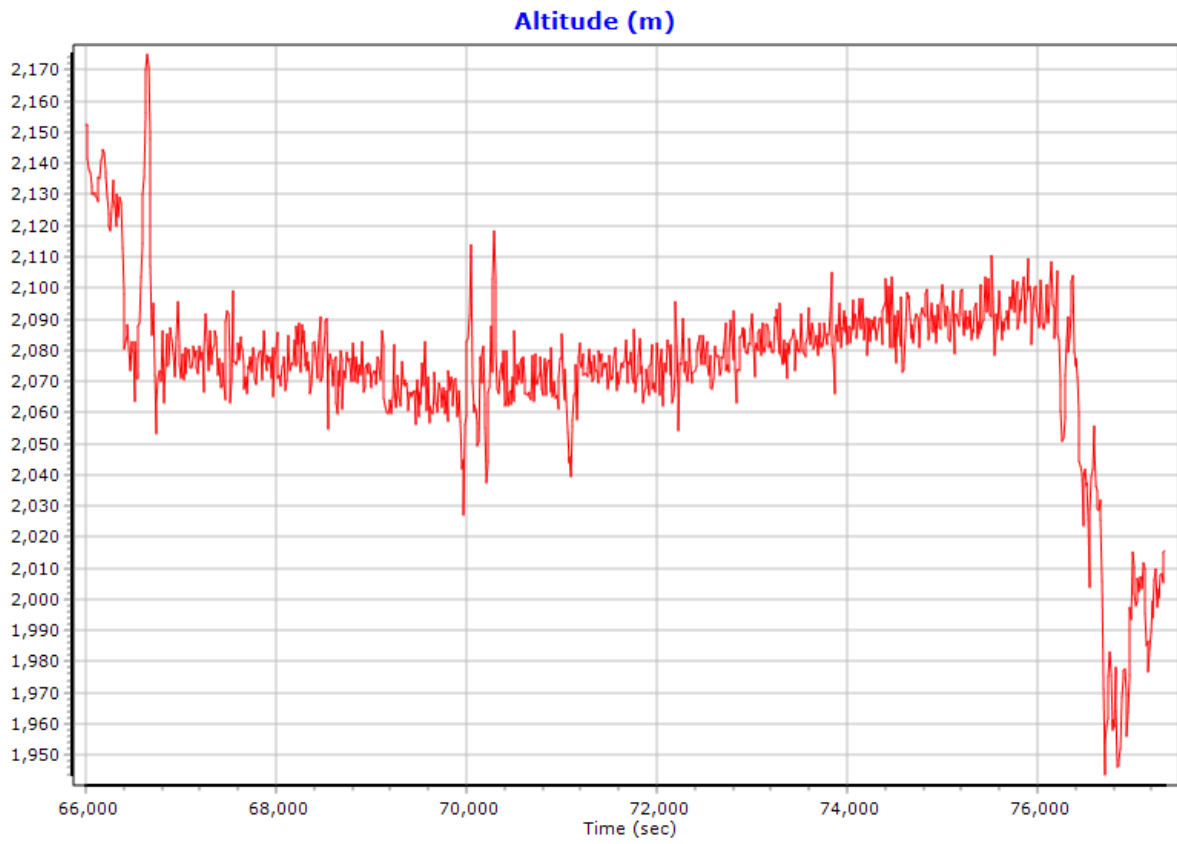
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	565413.000	575678.000	10265.000	End of file

OK Cancel

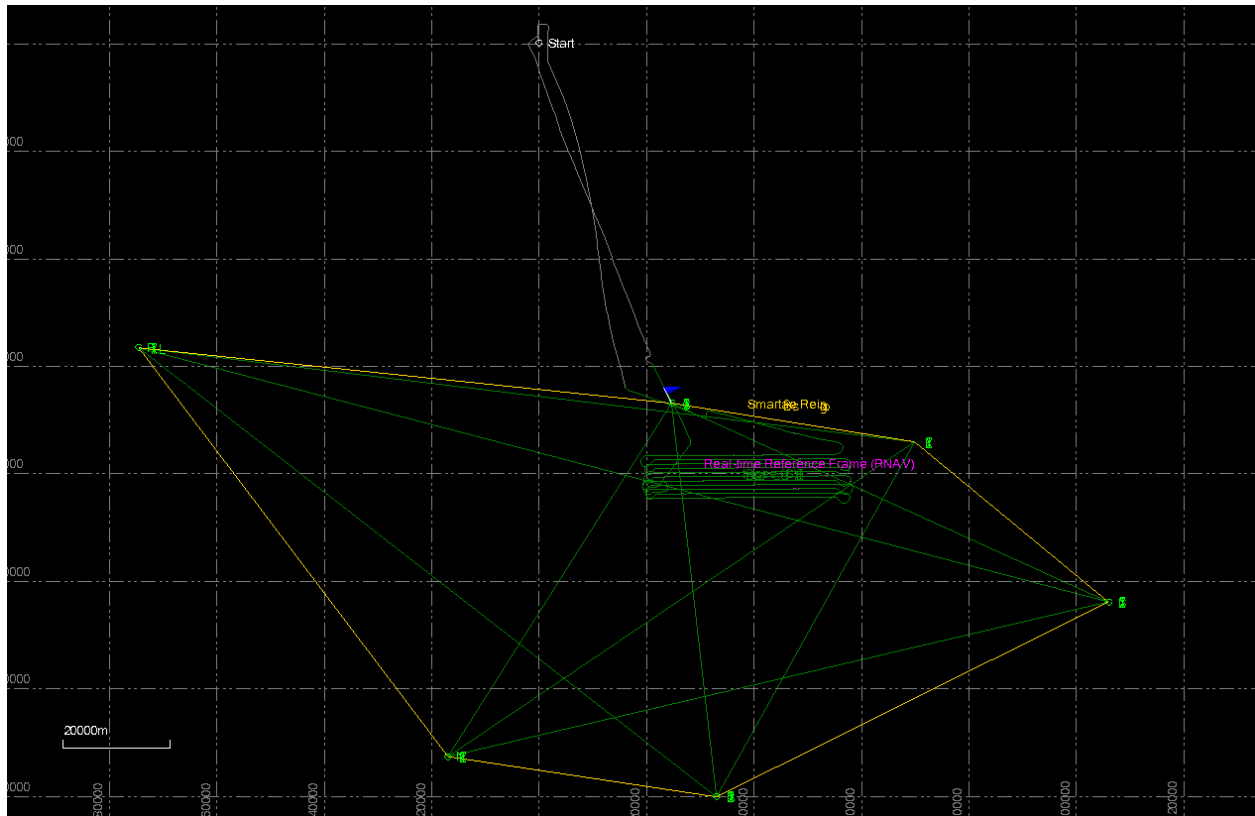
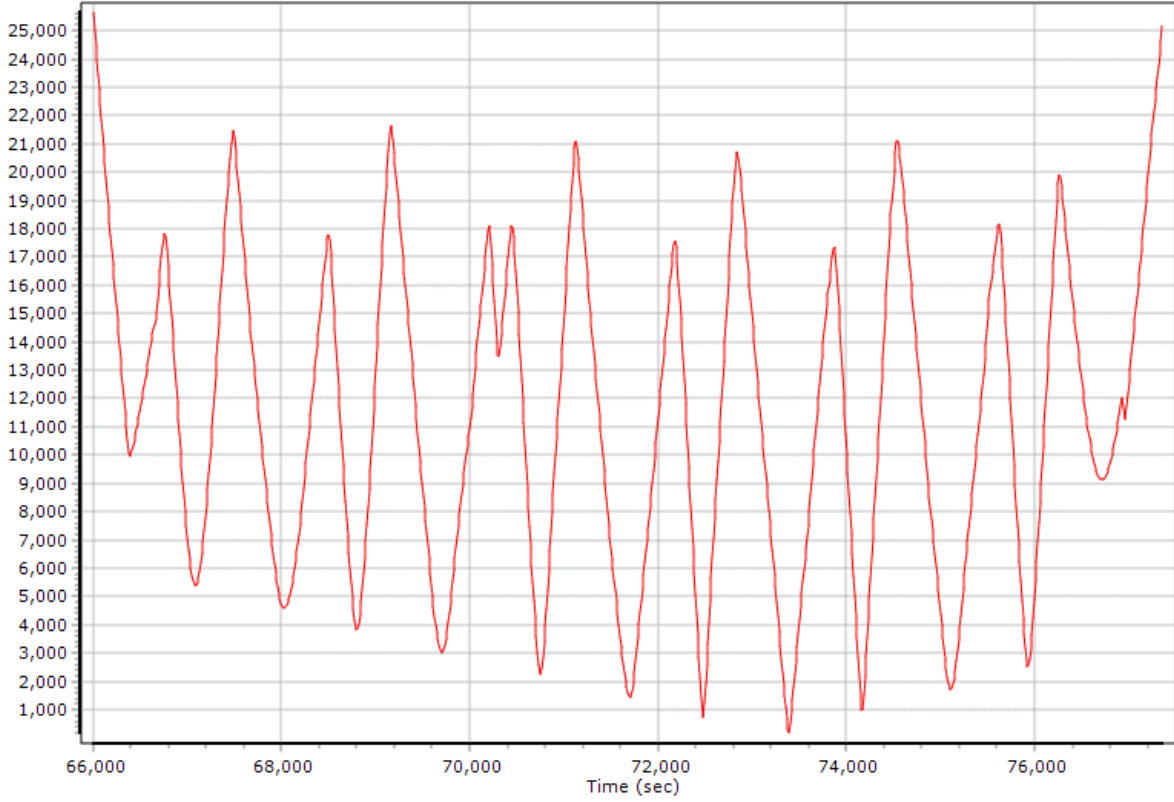
CAU18077A

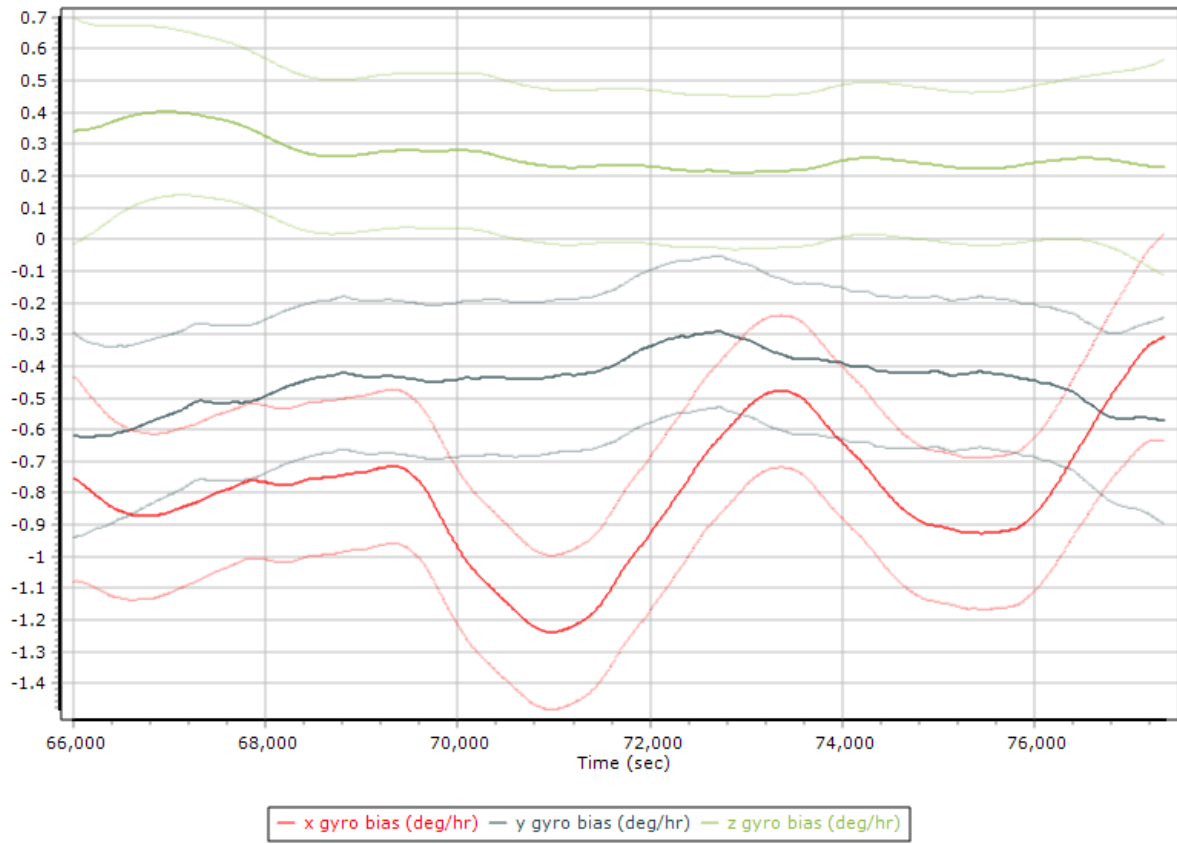


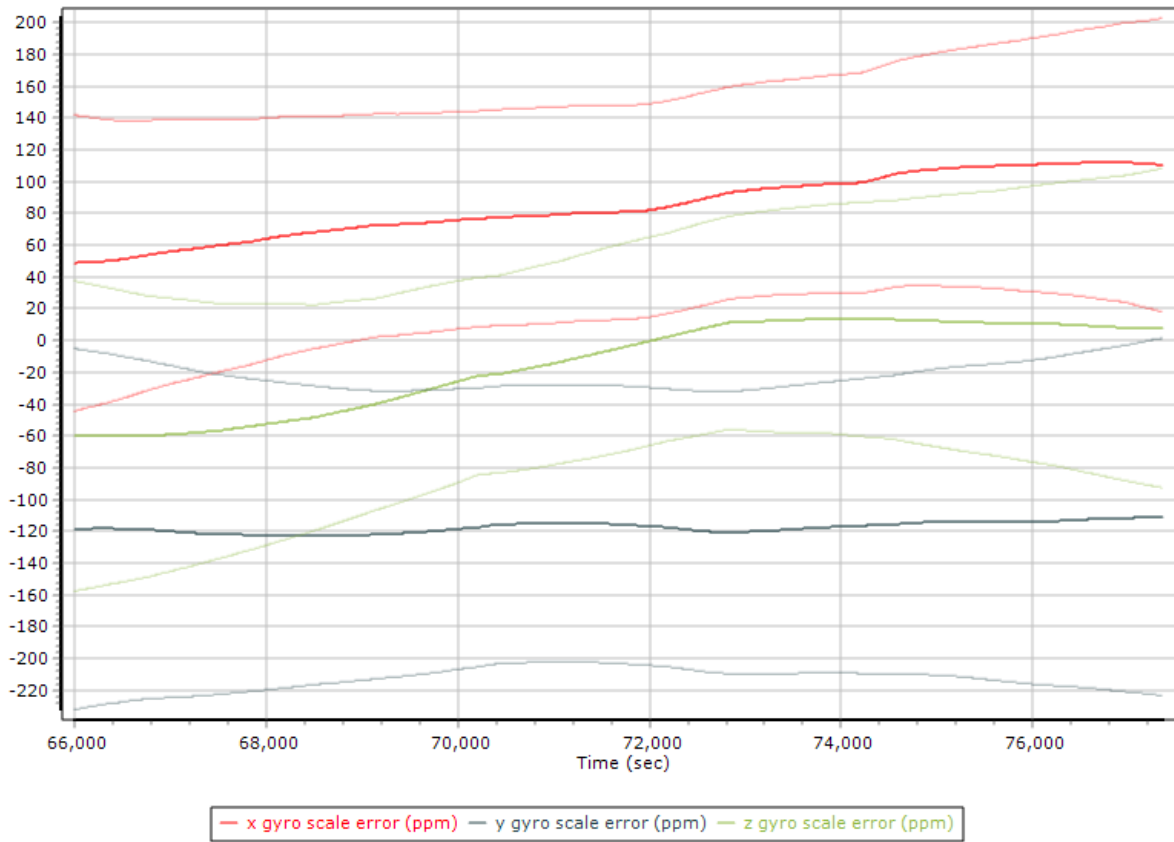




Baseline Length (m)







Project Settings

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- LiDAR
- SAR

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

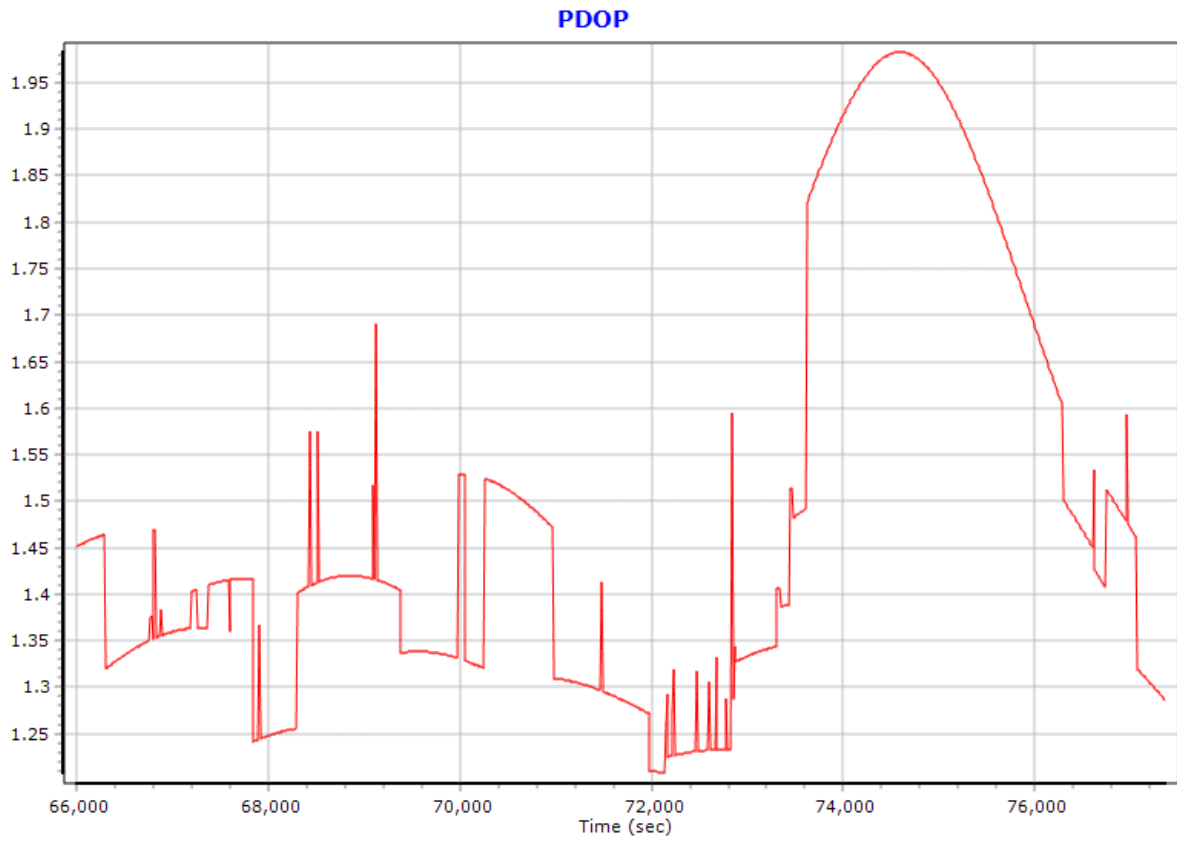
Aircraft to Reference Mounting Angles

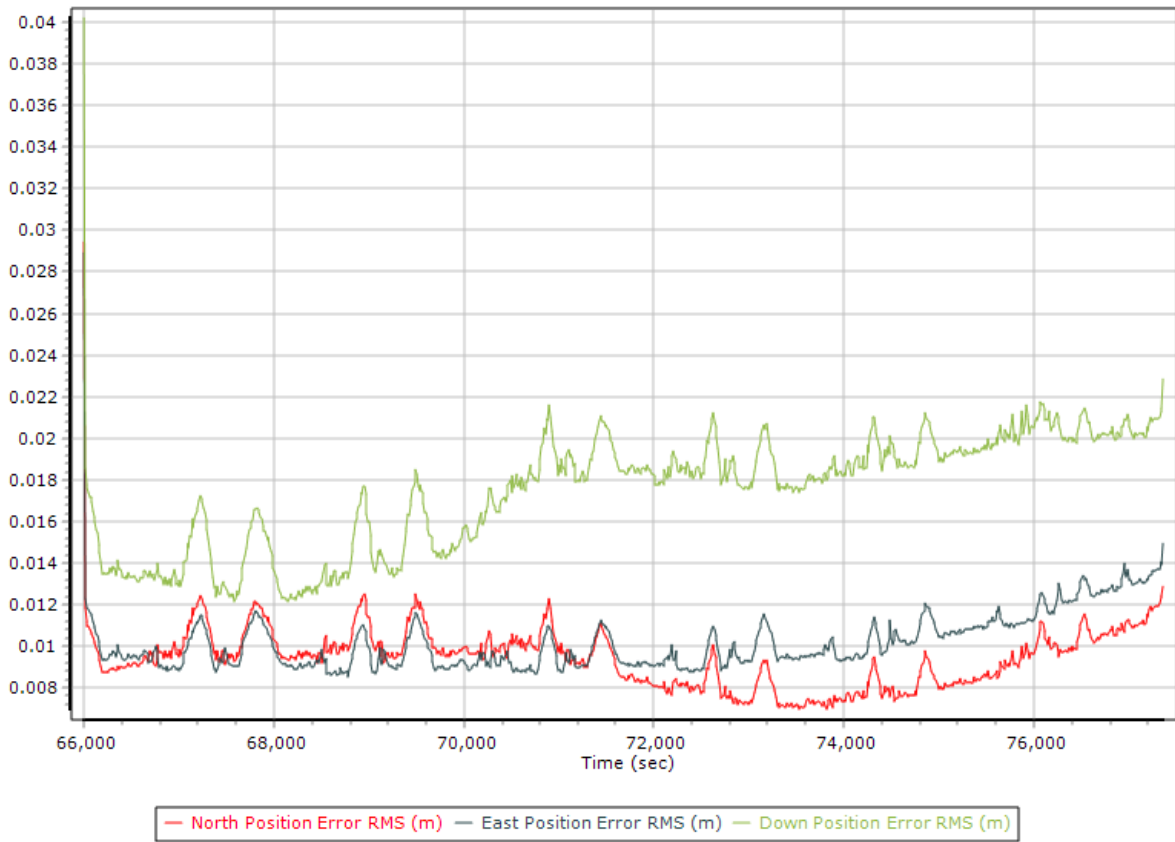
X:

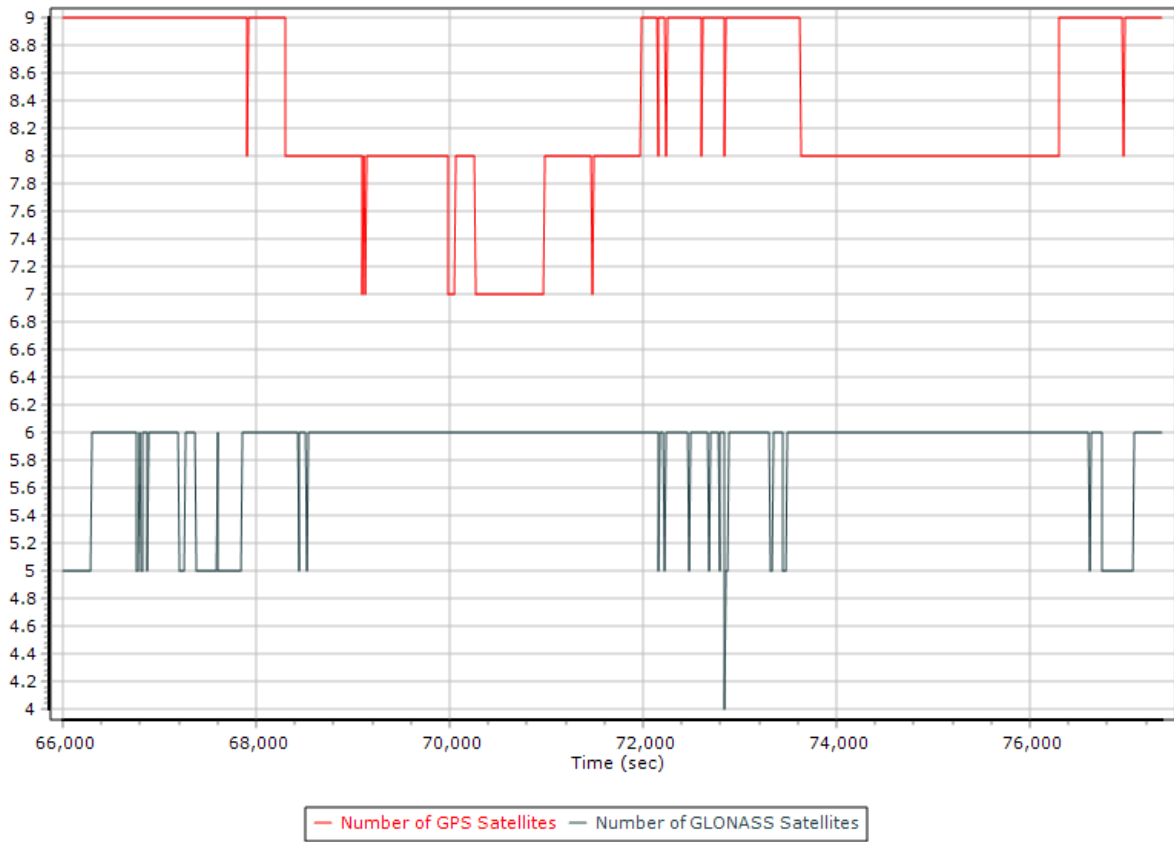
Y:

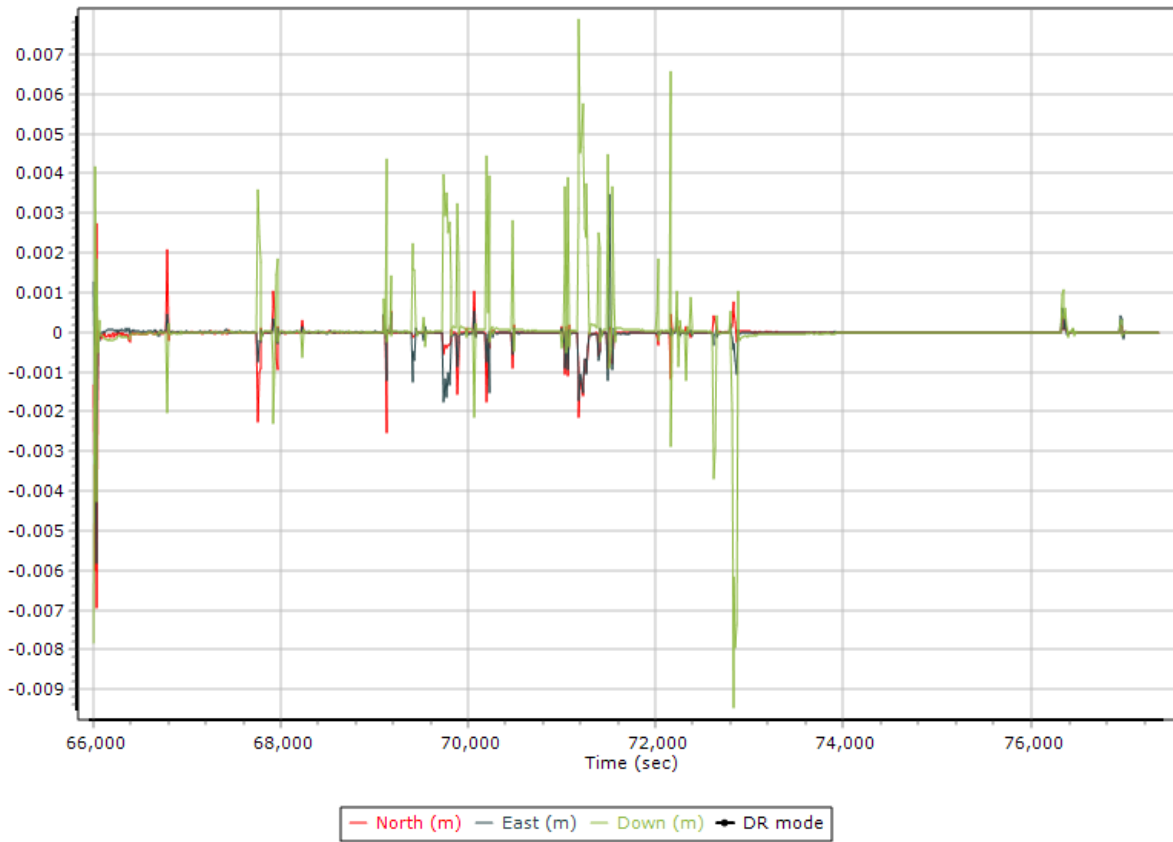
Z:

OK Cancel









Project Settings

- General Information
- Units
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- Export
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- SAR

Timing

Start: 63795.000
 End: 78920.000

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

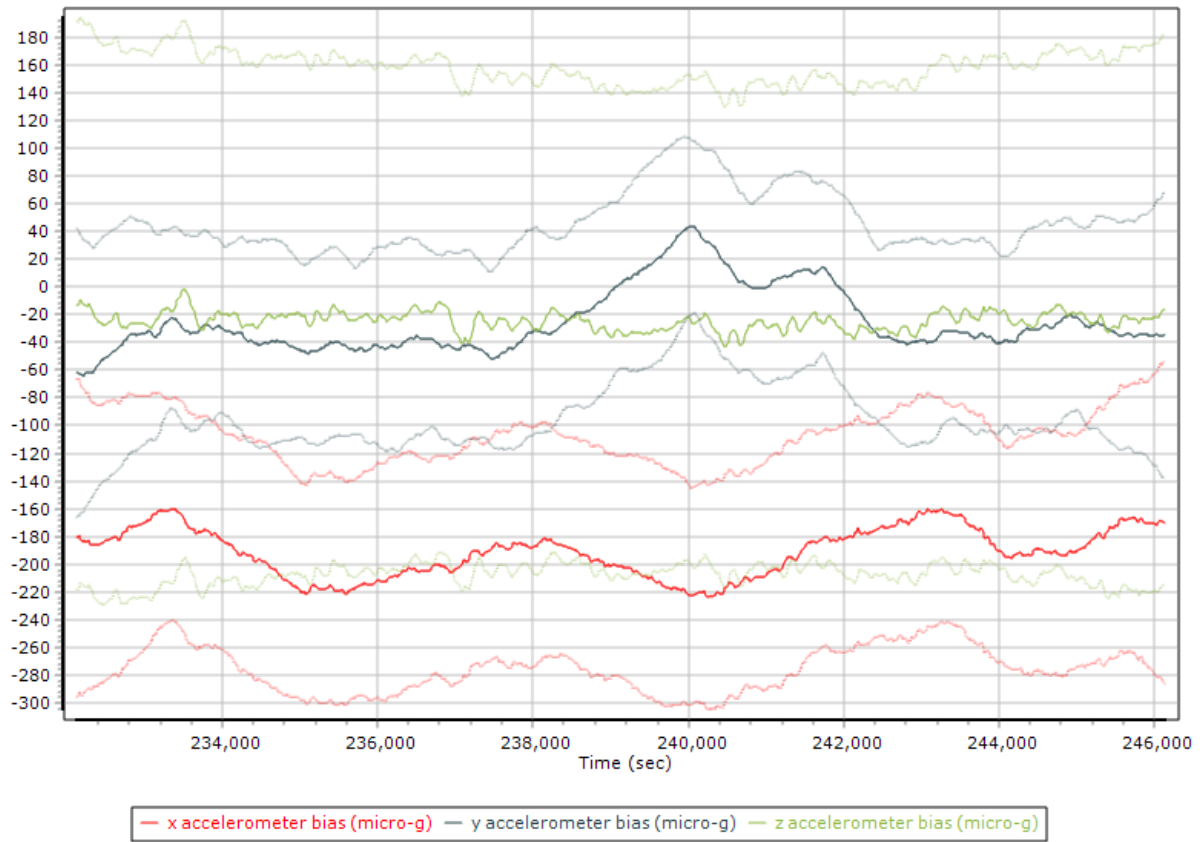
Processable Time Windows

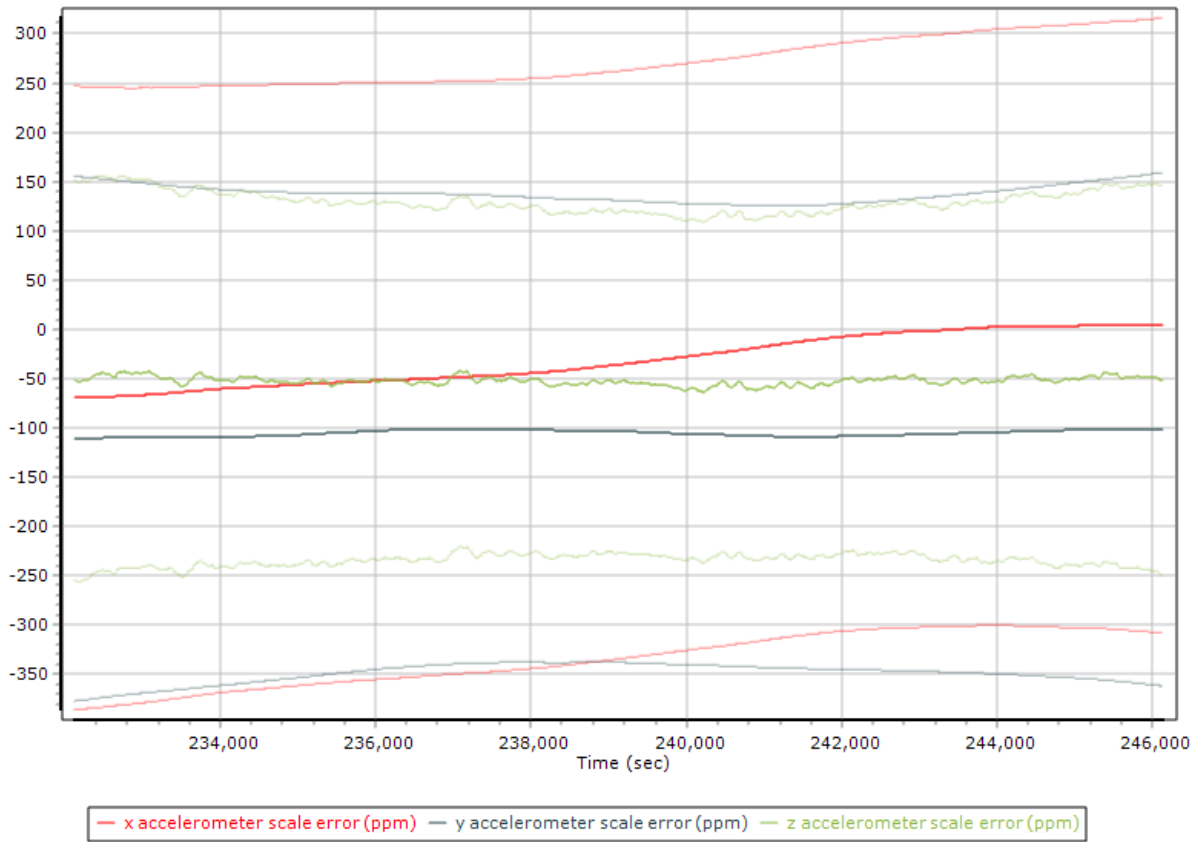
Start after launch Wait Time: 4.000 sec

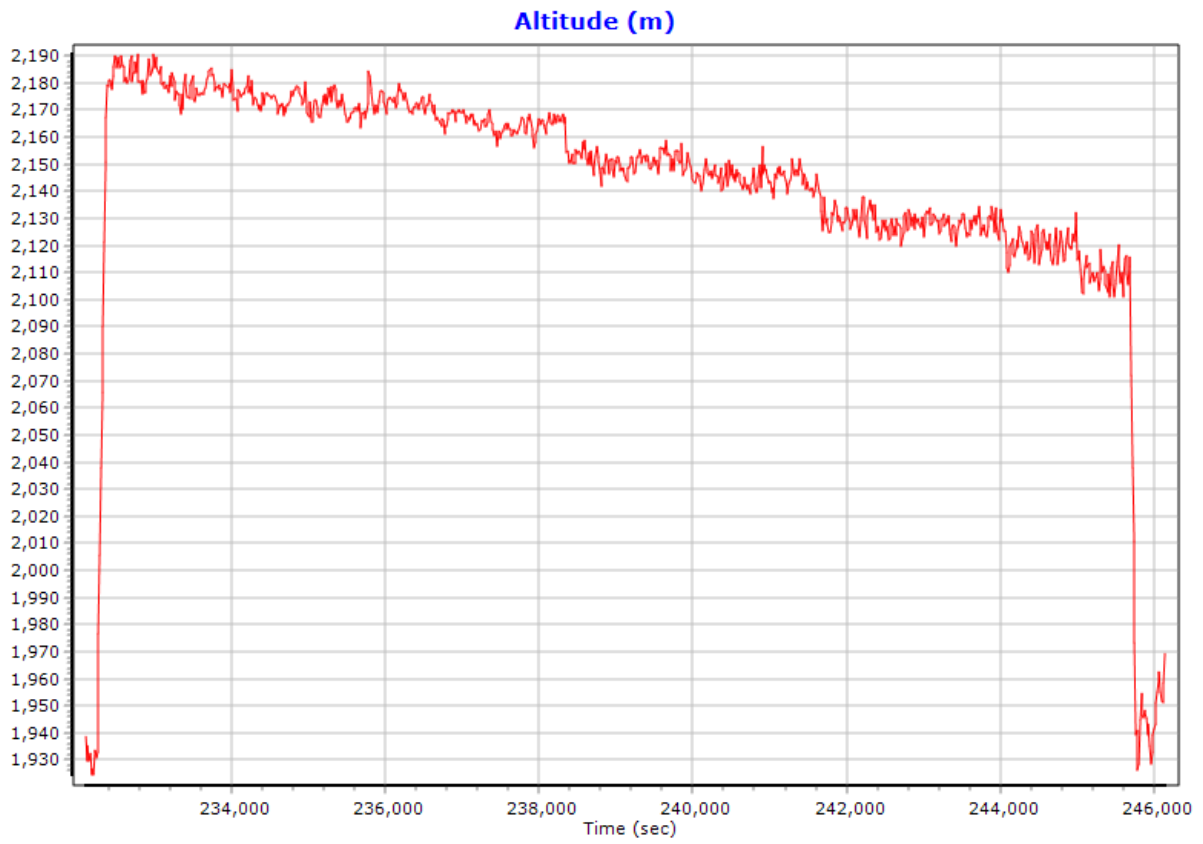
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	63795.000	78920.000	15125.000	End of file

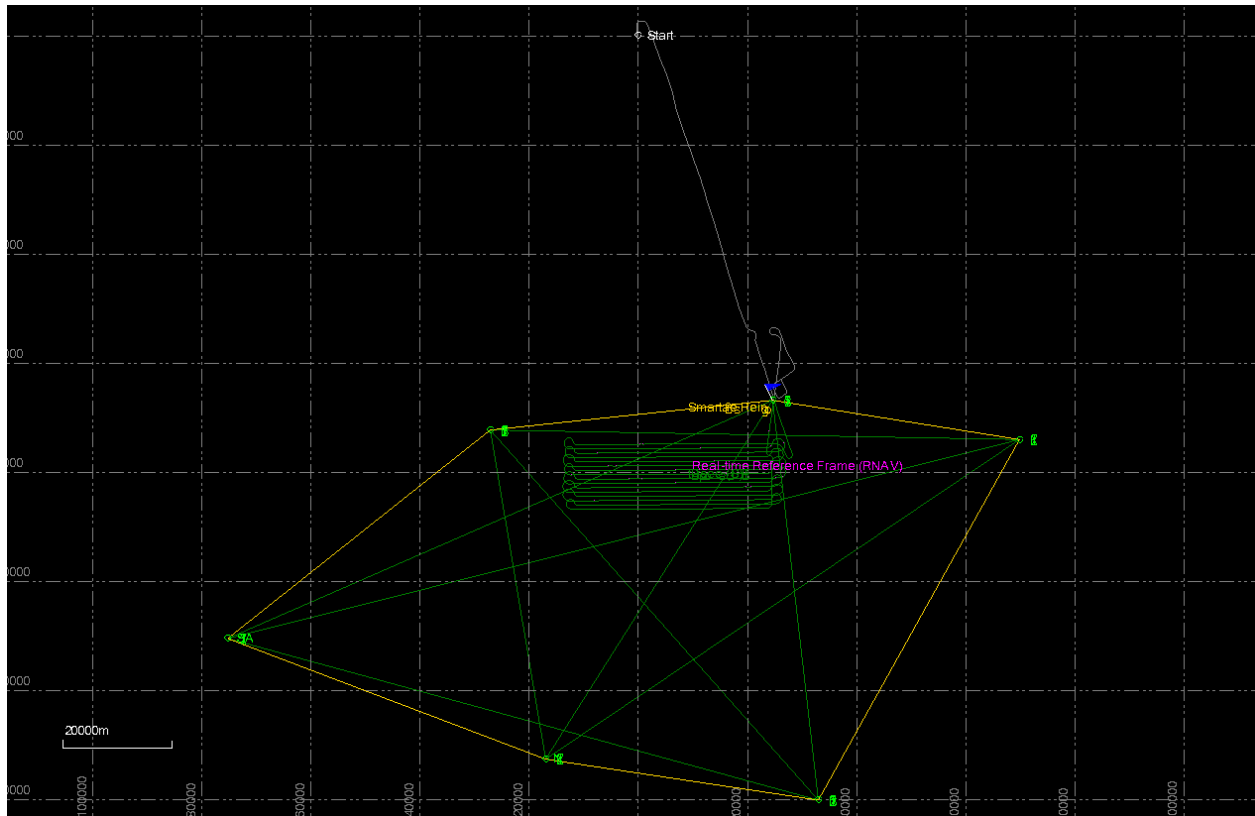
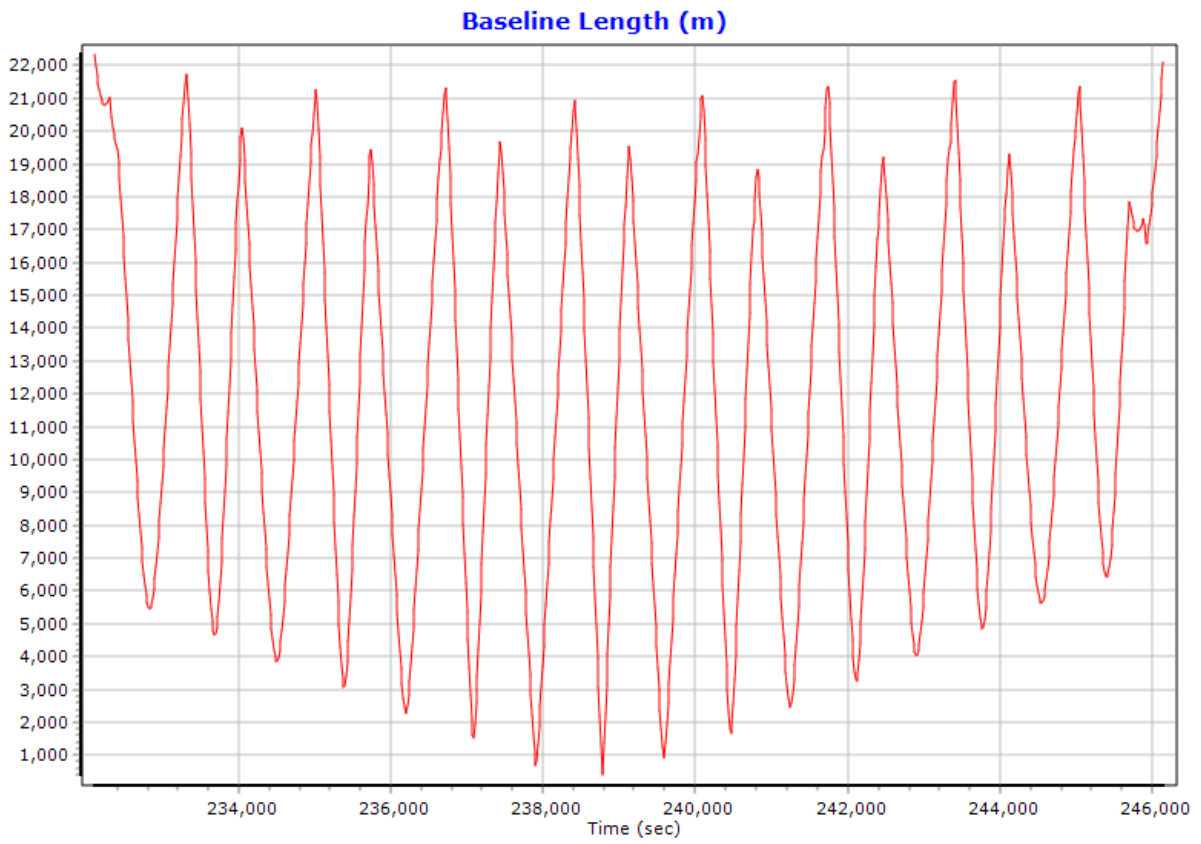
OK Cancel

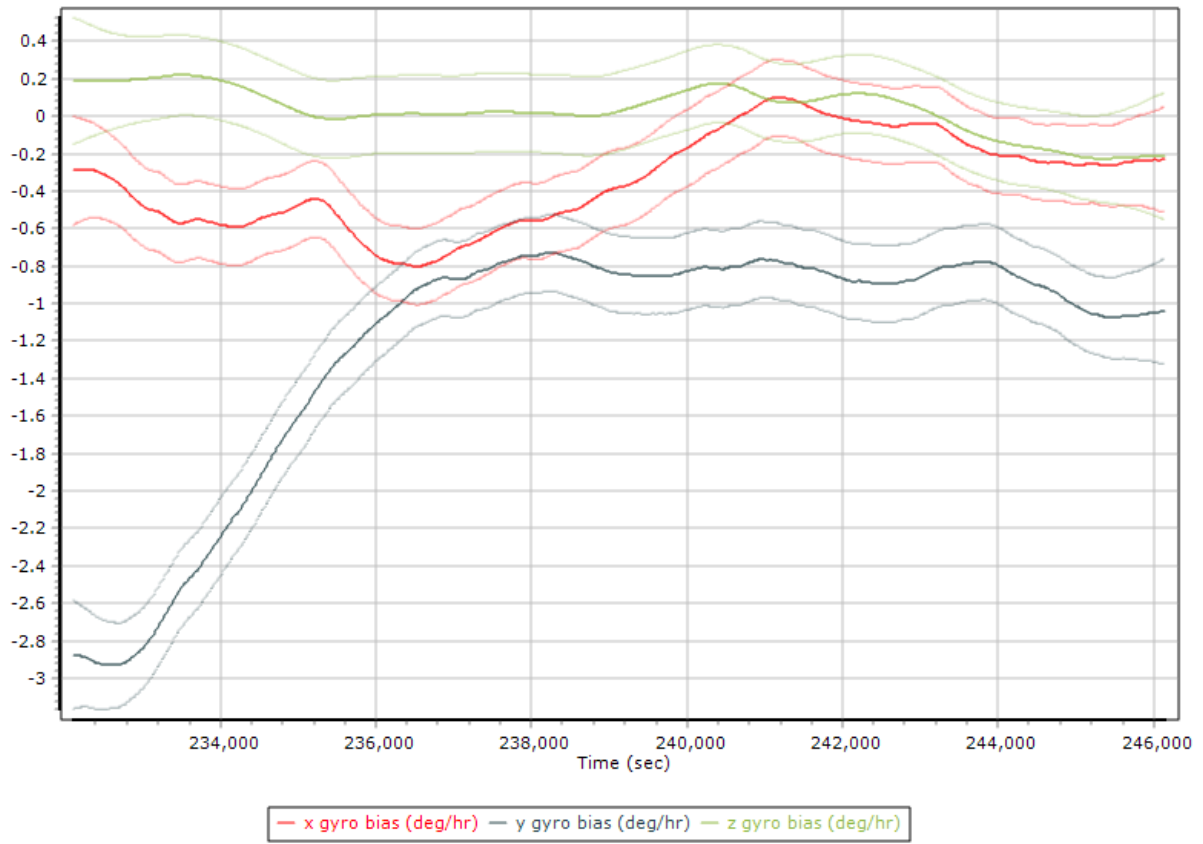
CAU18079A

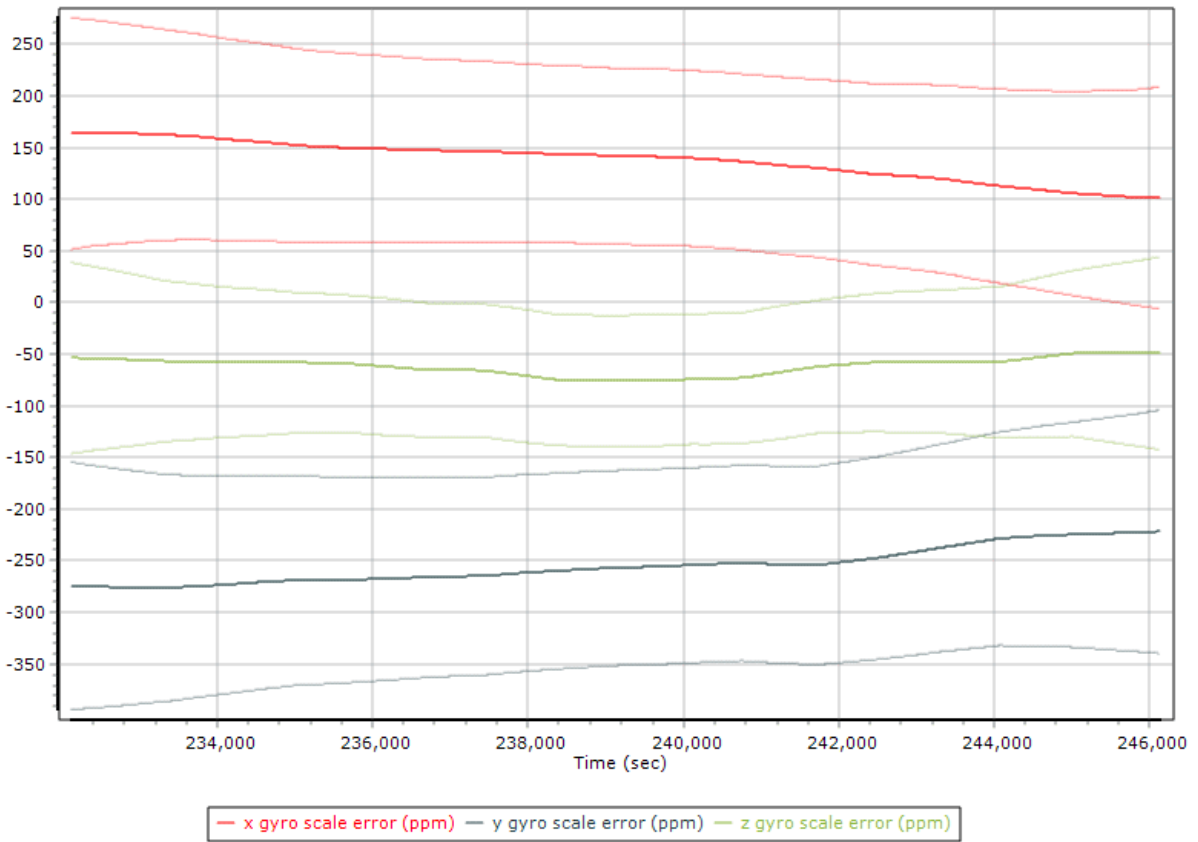












Project Settings ✕

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- Camera
- LiDAR
- SAR

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

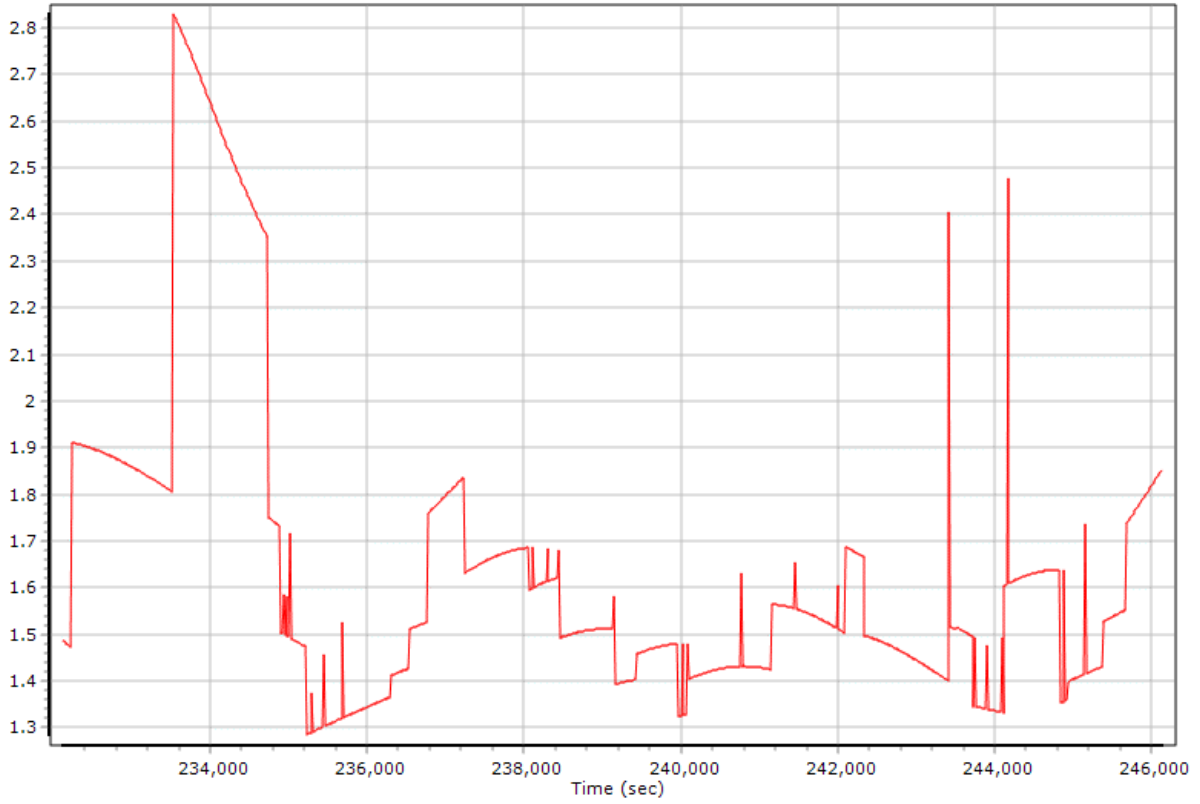
Aircraft to Reference Mounting Angles

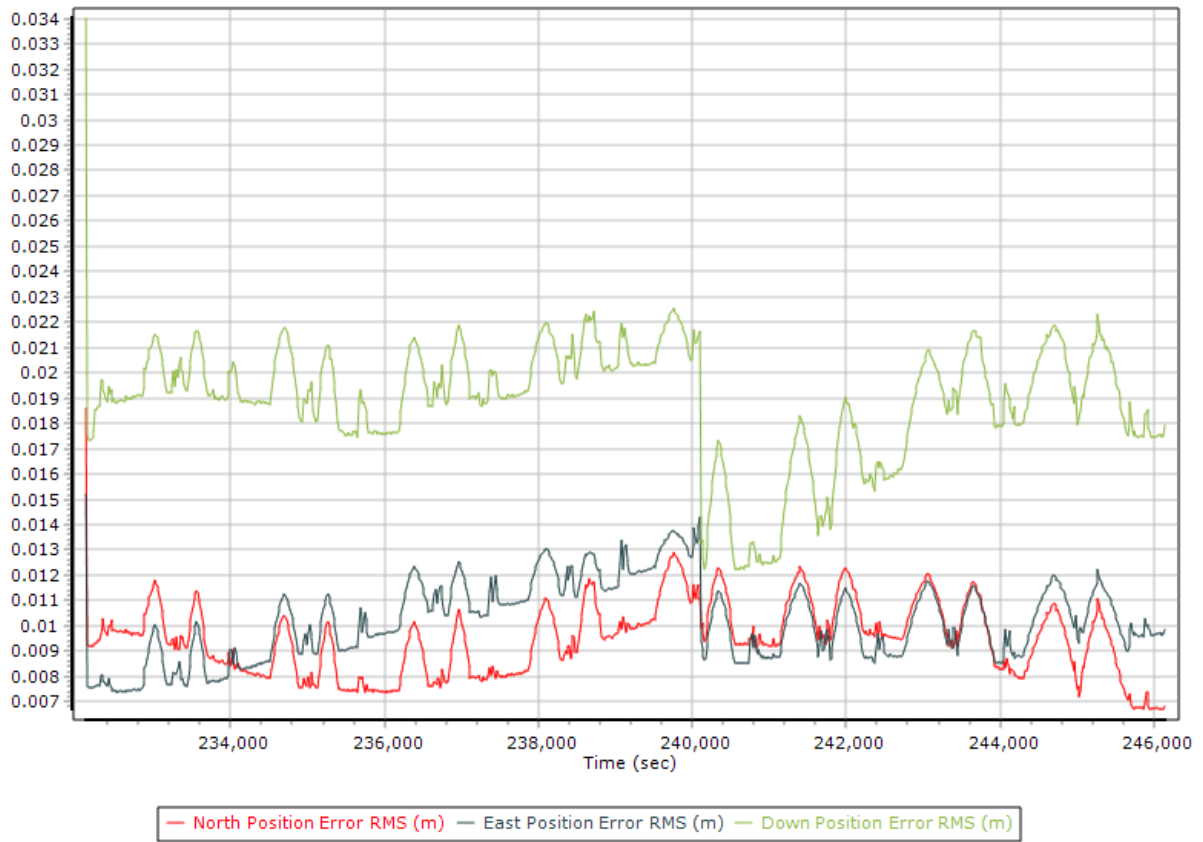
X:

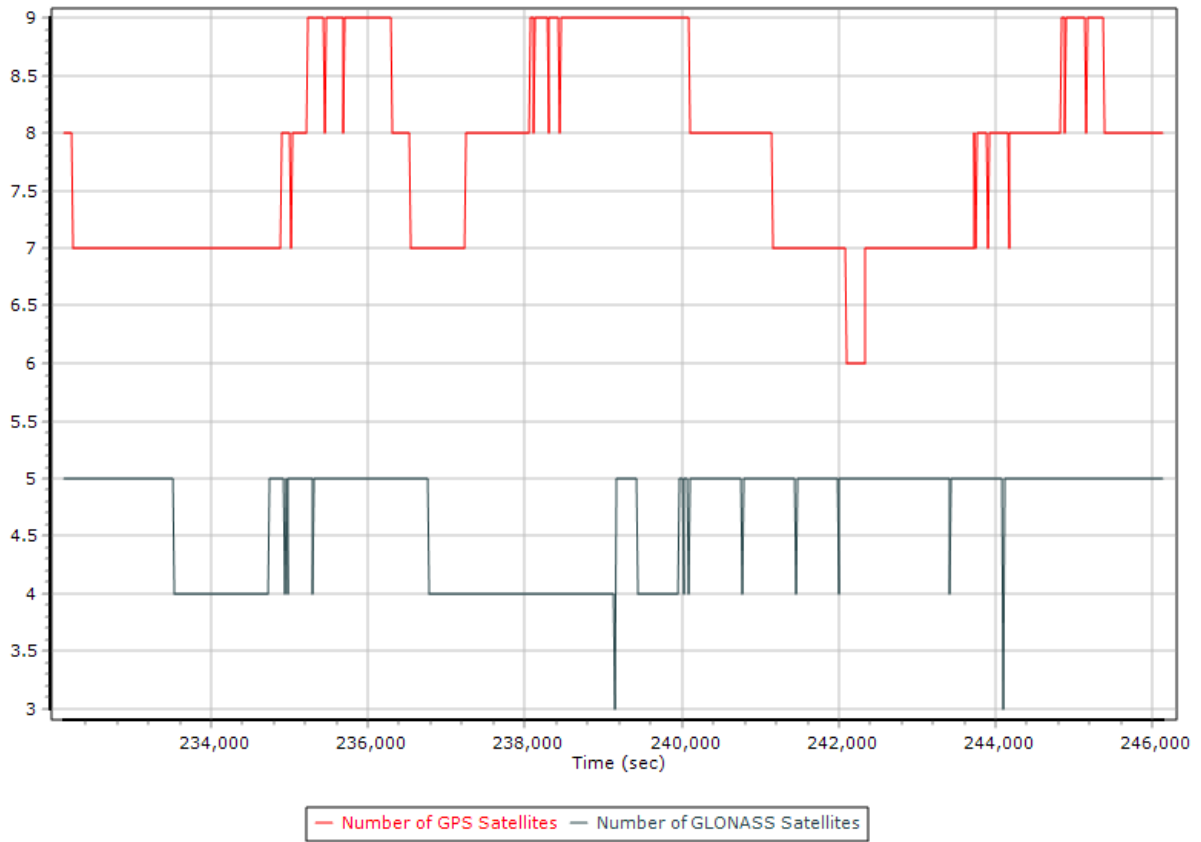
Y:

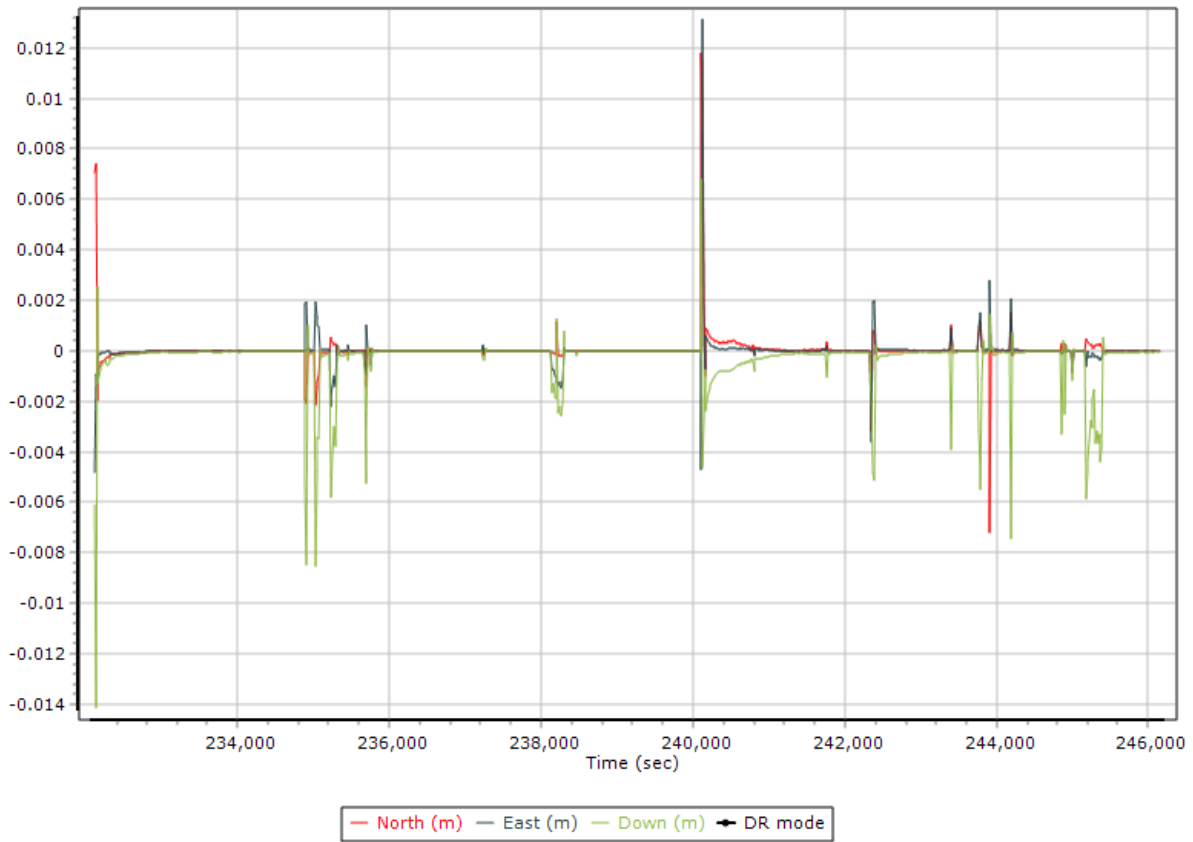
Z:

PDOP









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Timing

Start: 230003.000
End: 246942.000

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

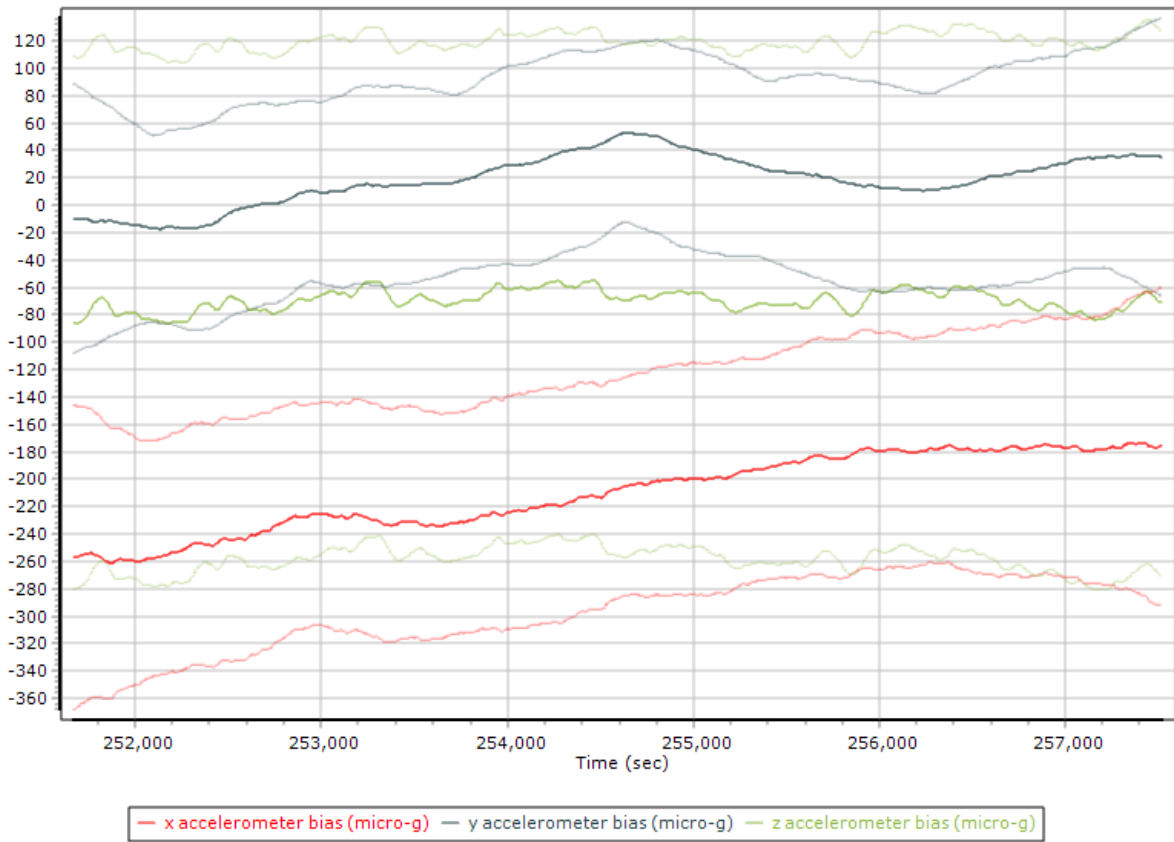
Processable Time Windows

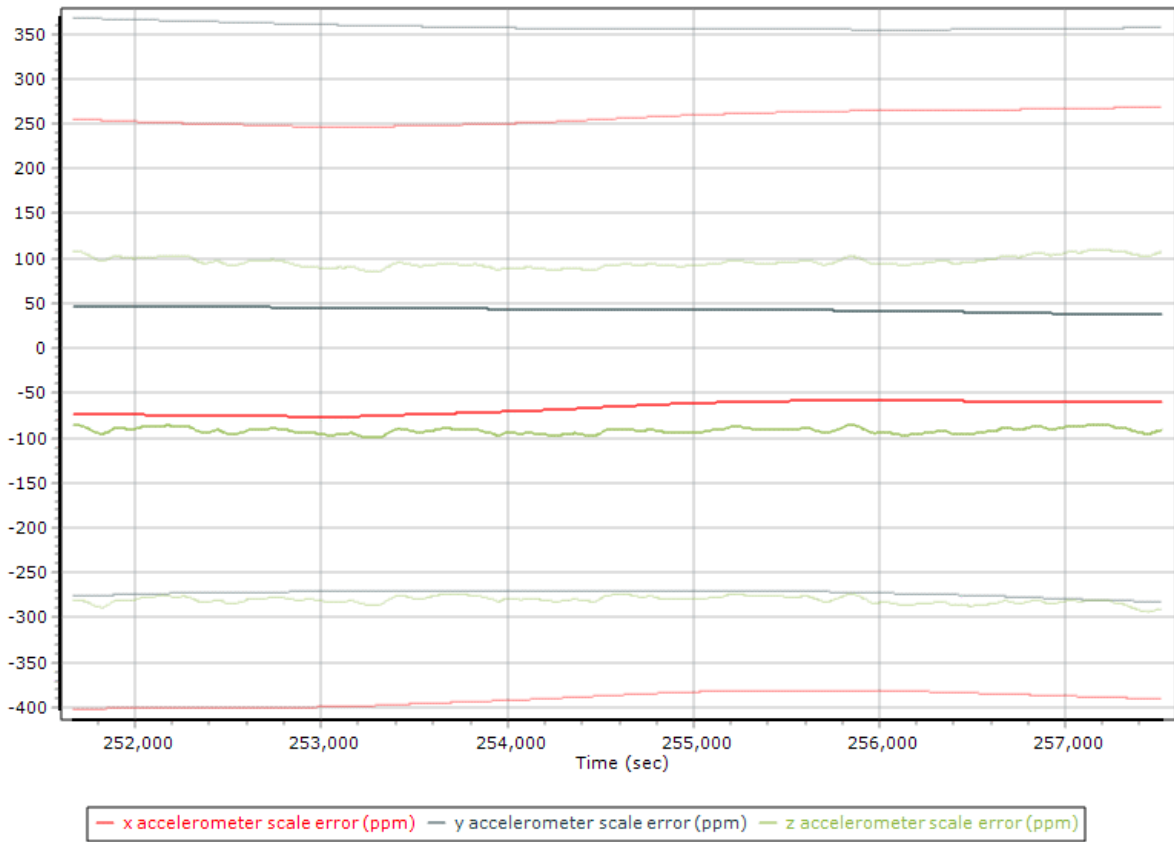
Start after launch Wait Time: 4.000 sec

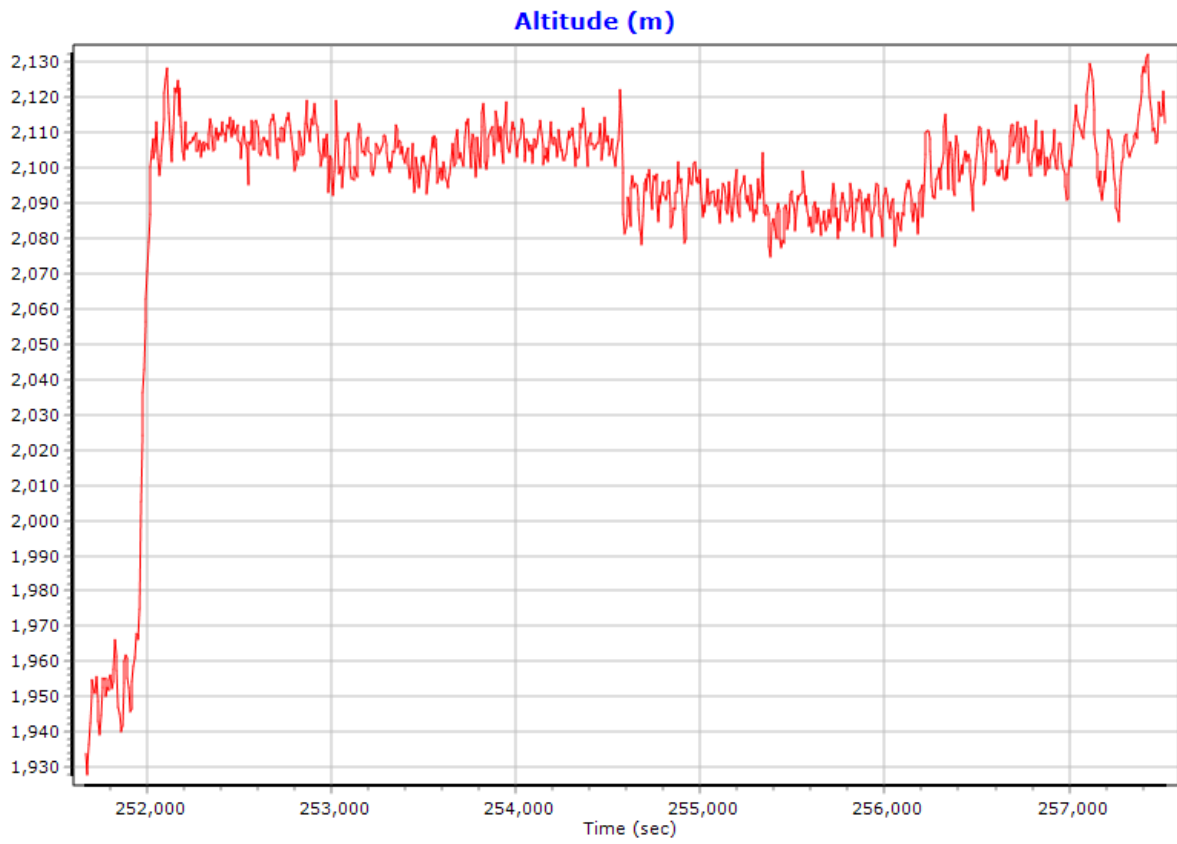
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	230003.000	246942.000	16939.000	End of file

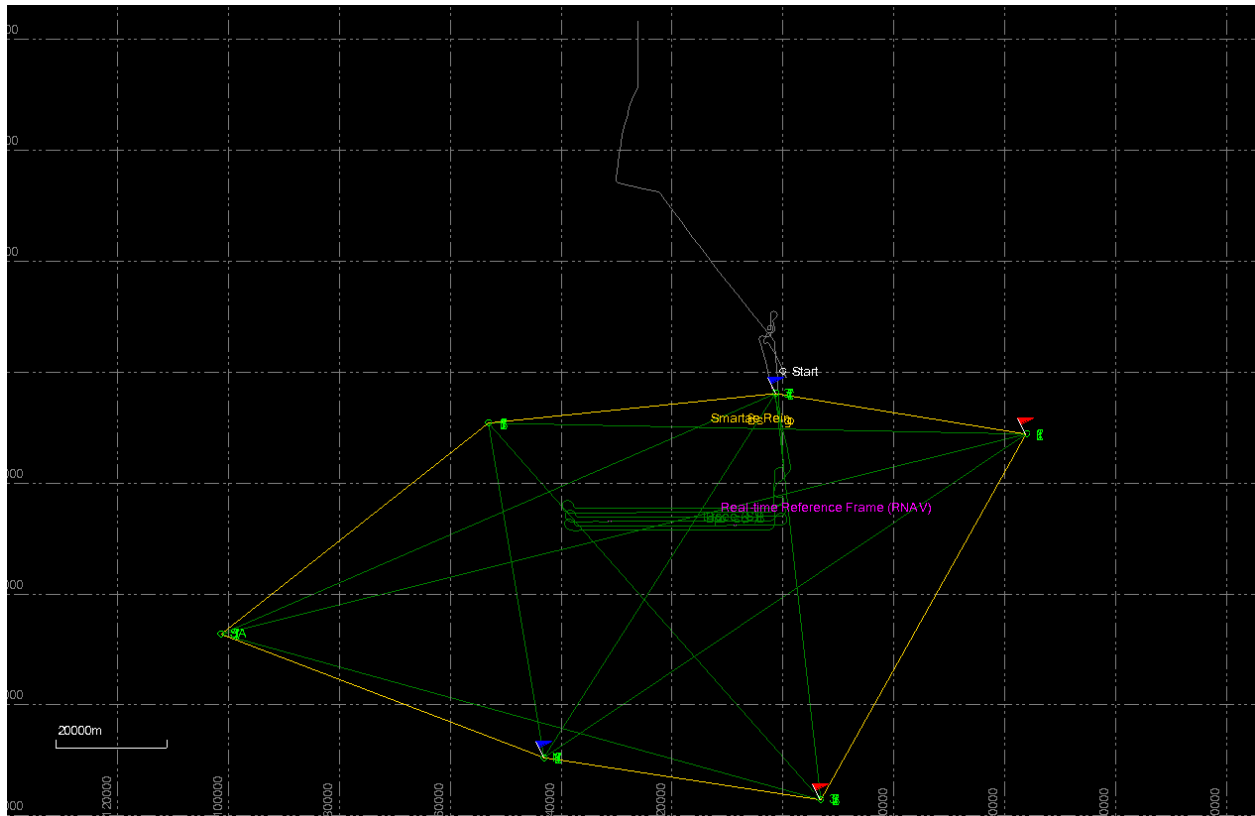
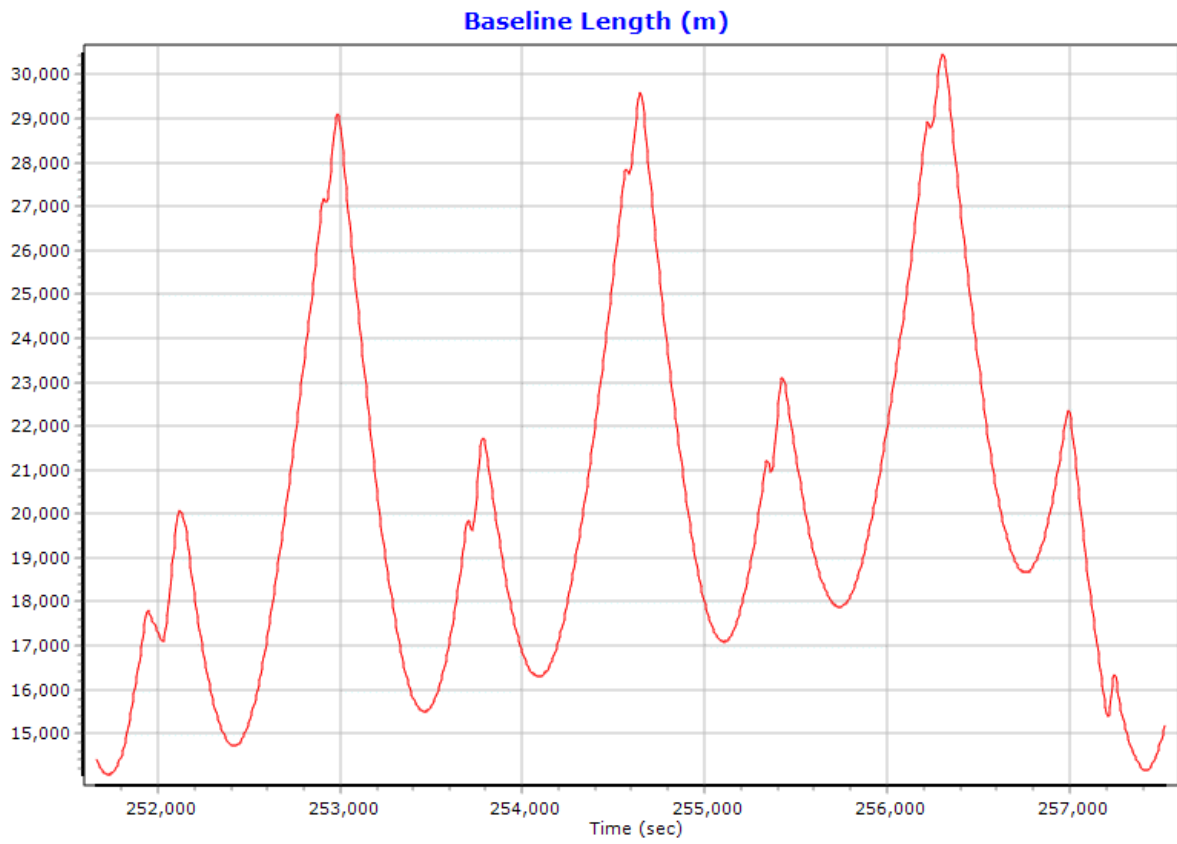
OK Cancel

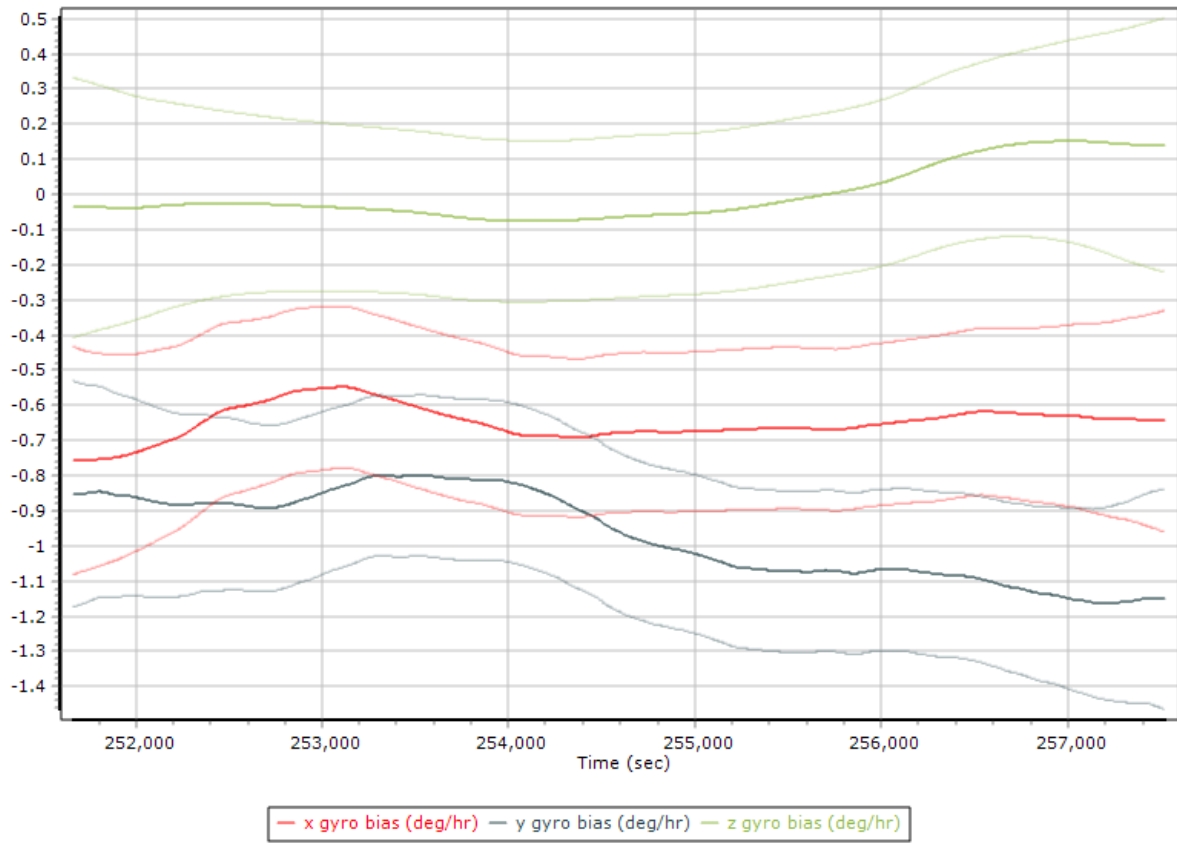
CAU18079B

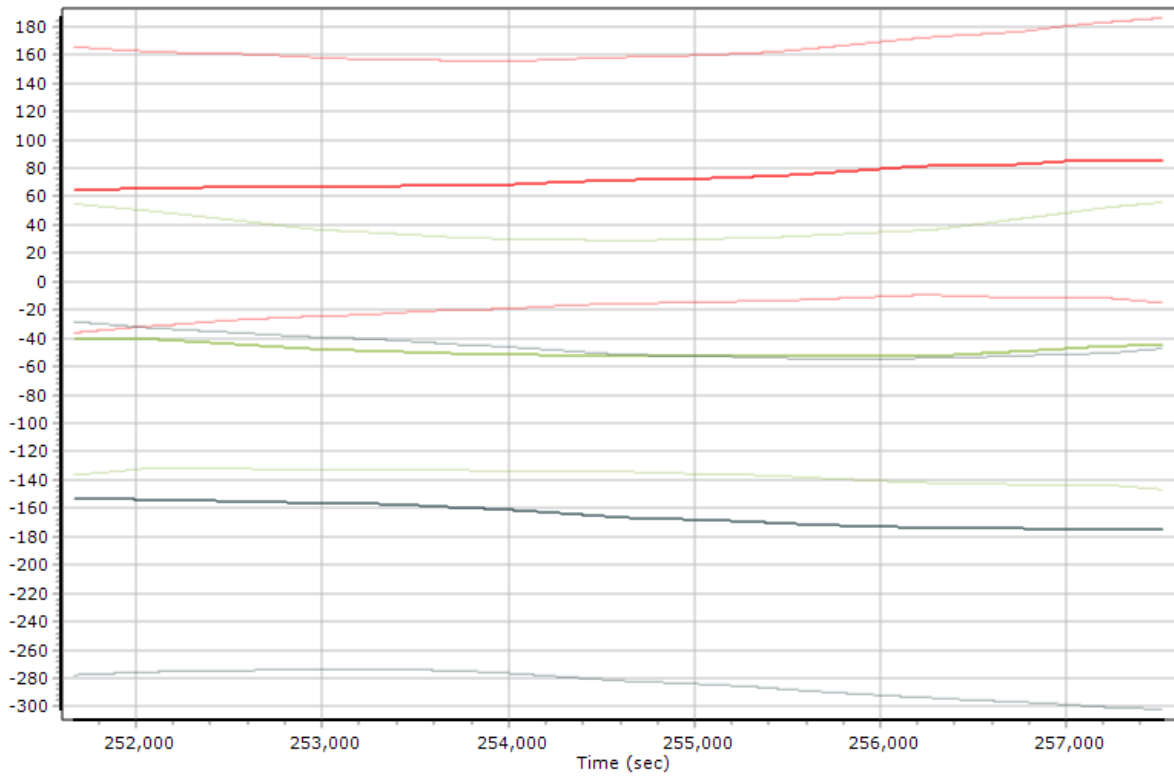












— x gyro scale error (ppm) — y gyro scale error (ppm) — z gyro scale error (ppm)

Project Settings ✕

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Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

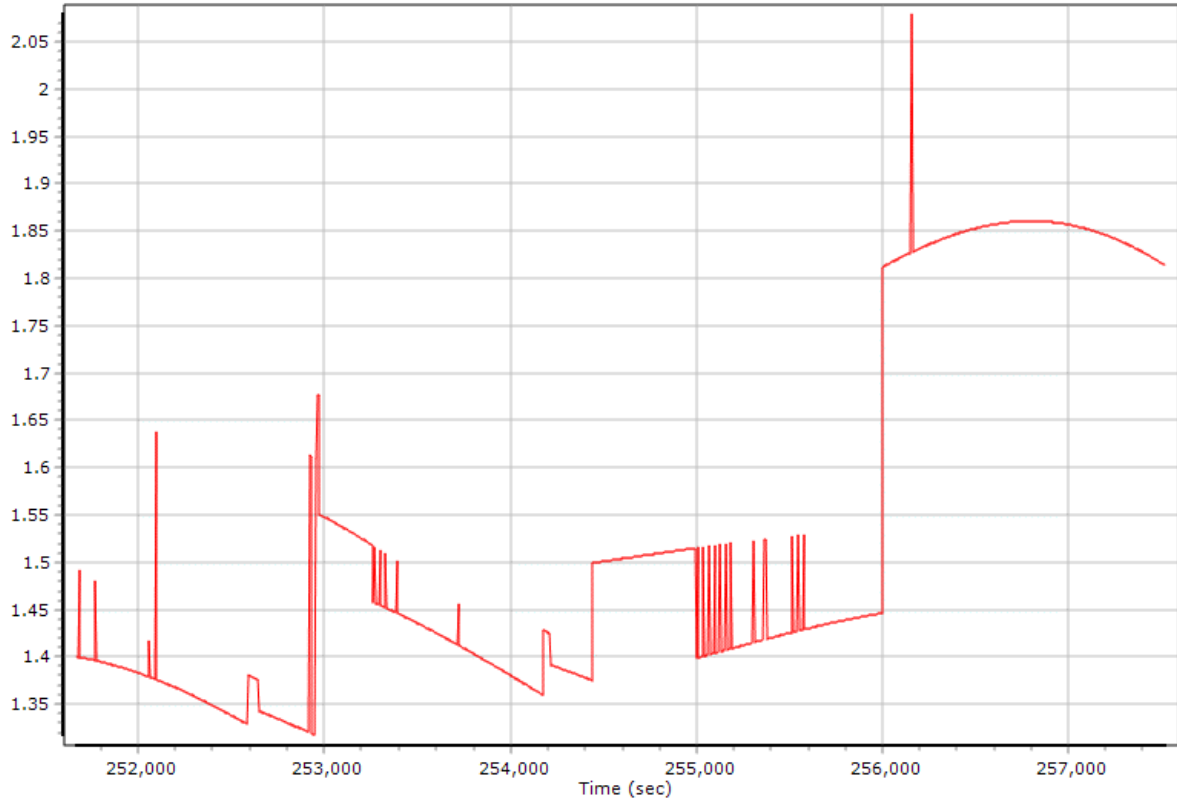
Aircraft to Reference Mounting Angles

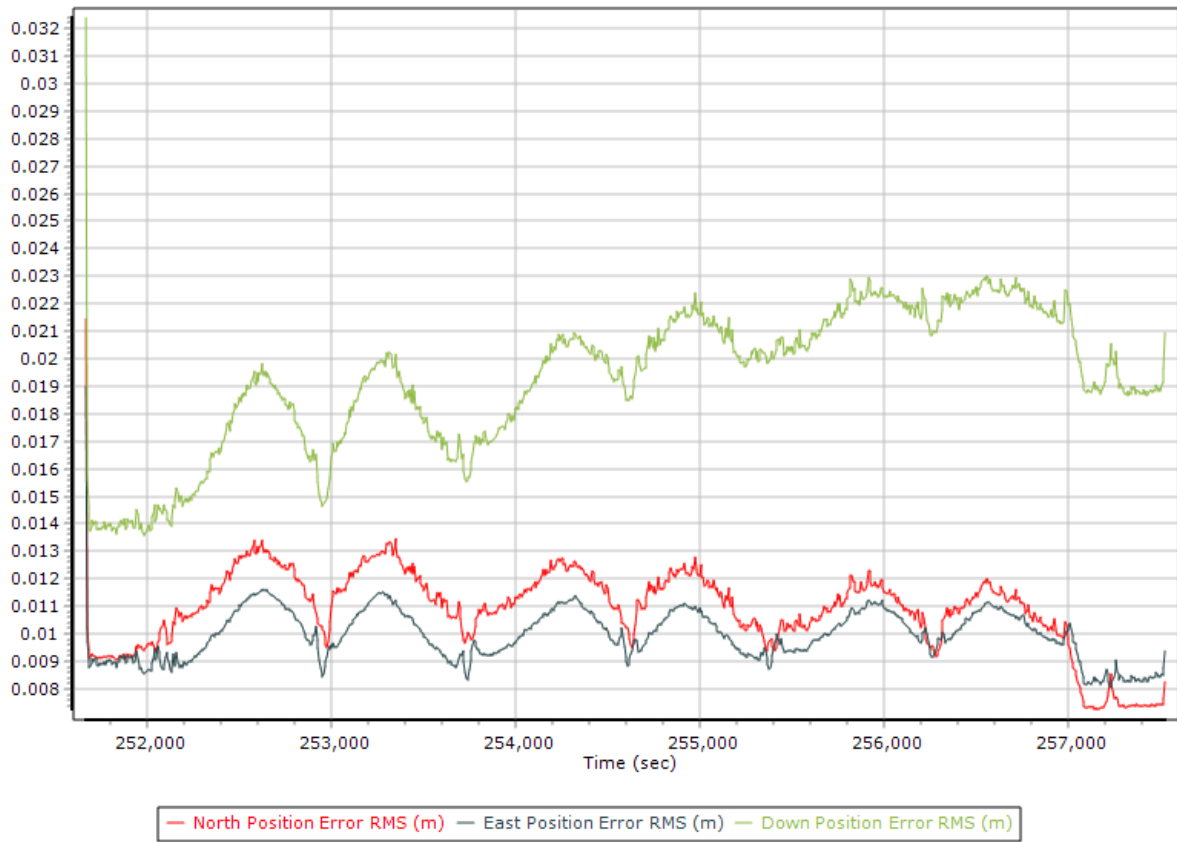
X:

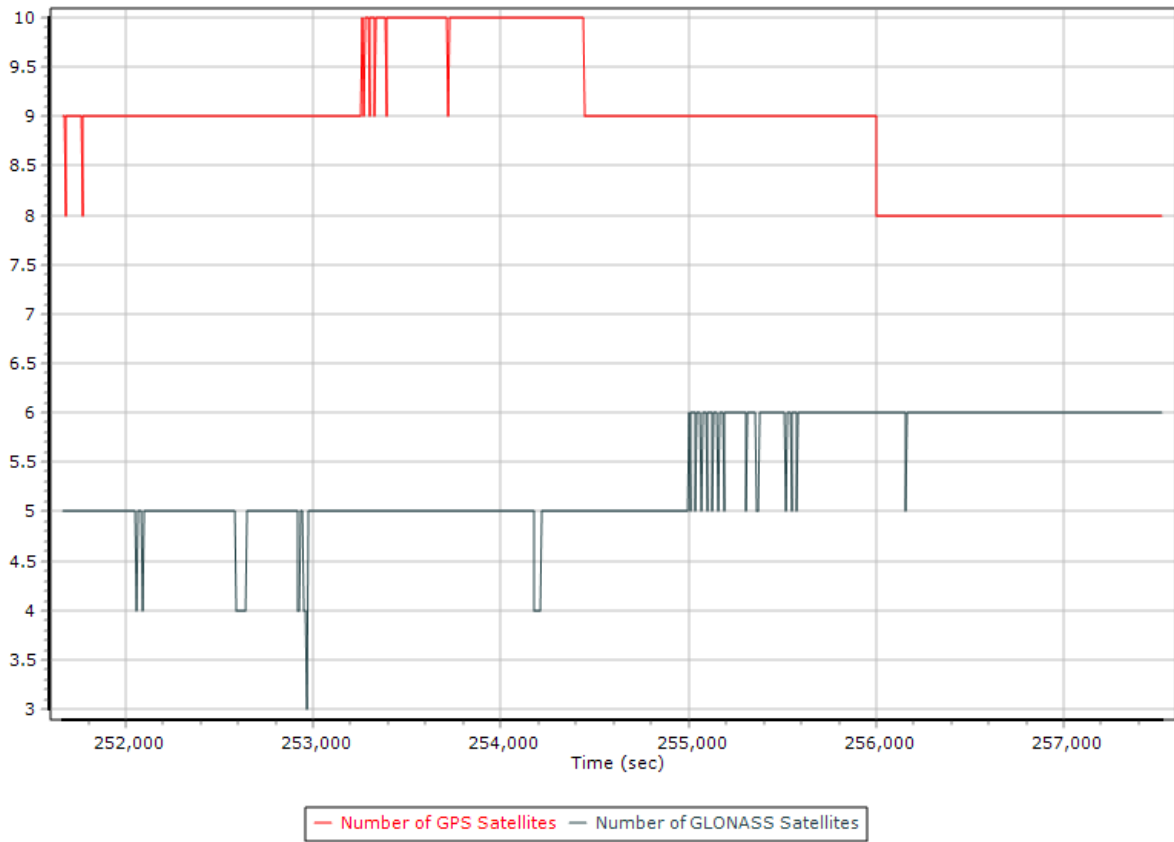
Y:

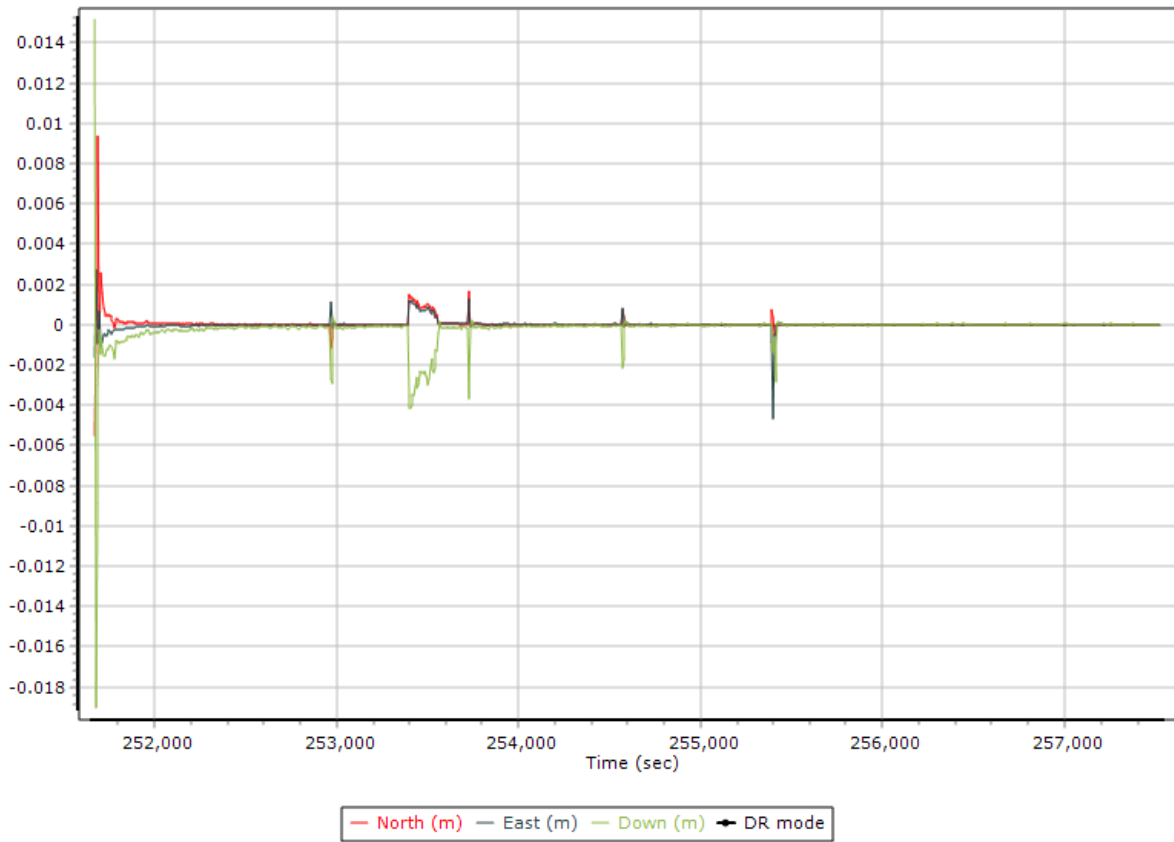
Z:

PDOP









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- SAR

Timing

Start: 250340.000
 End: 259221.000

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

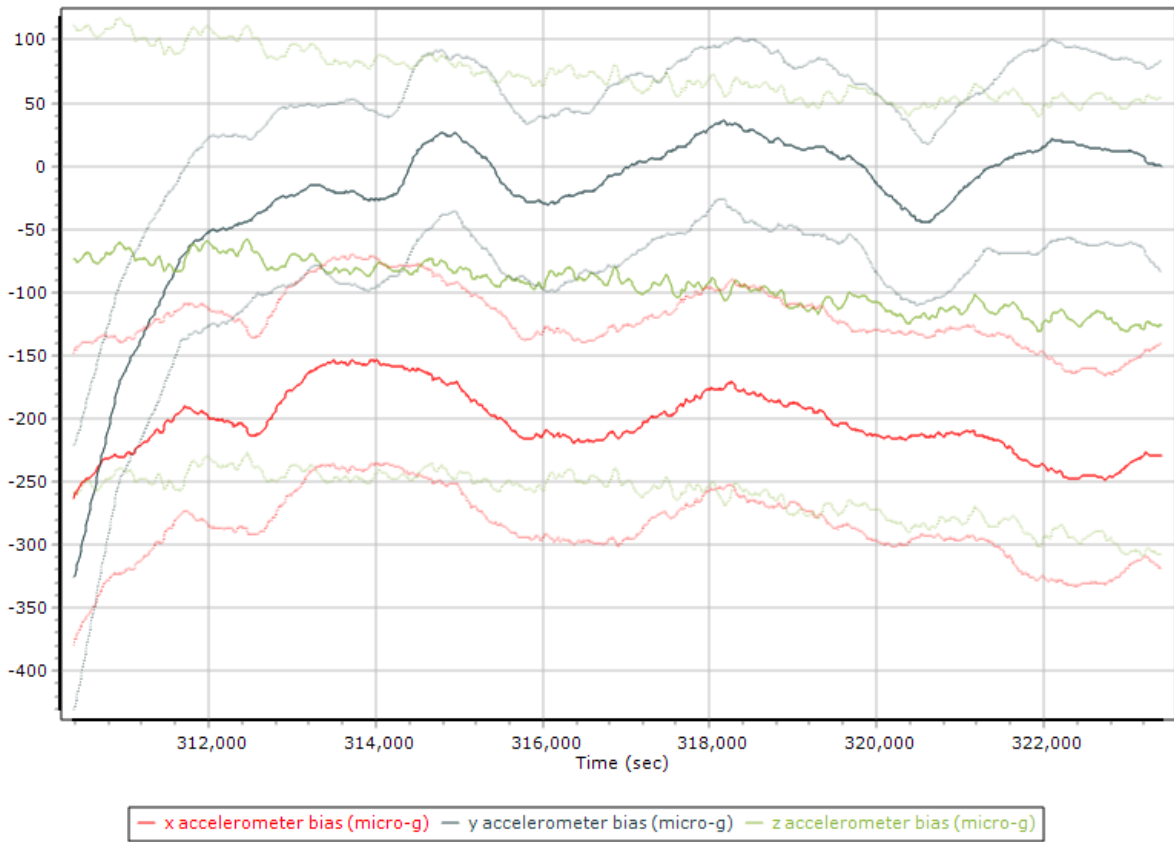
Processable Time Windows

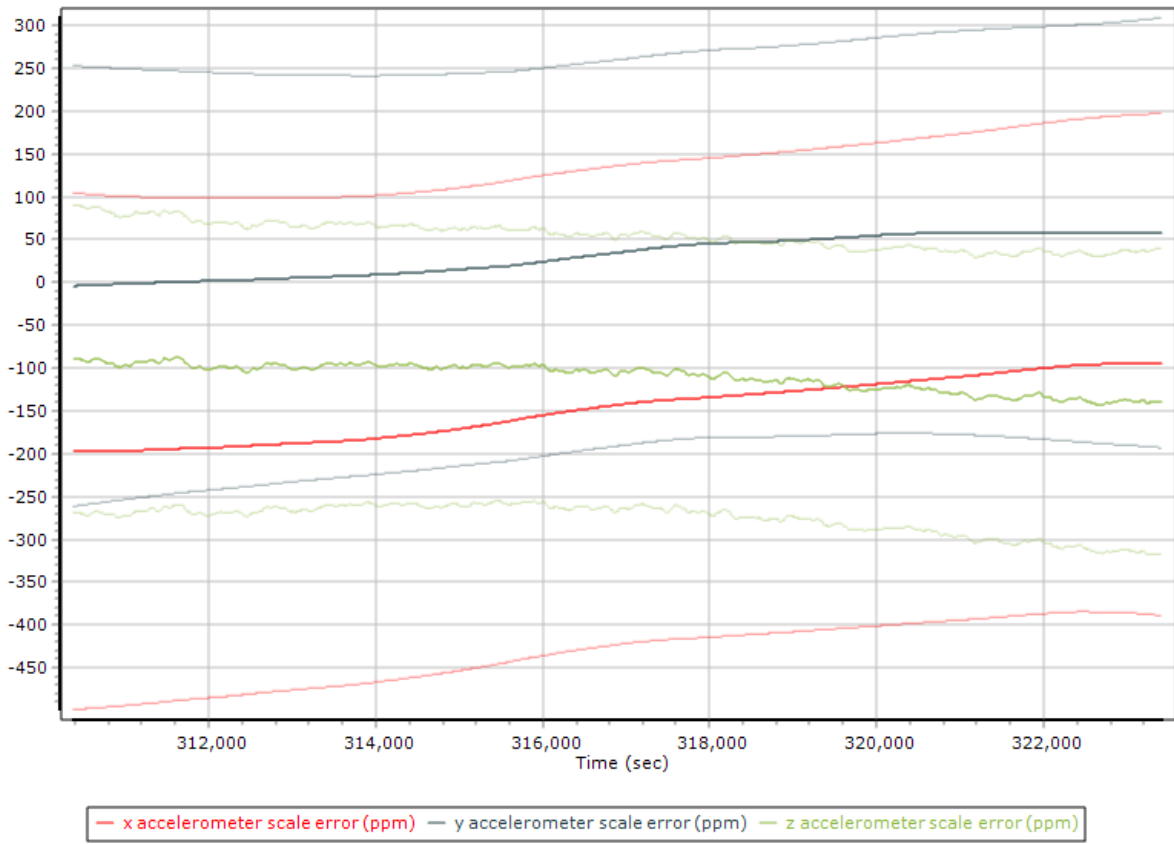
Start after launch Wait Time: 4.000 sec

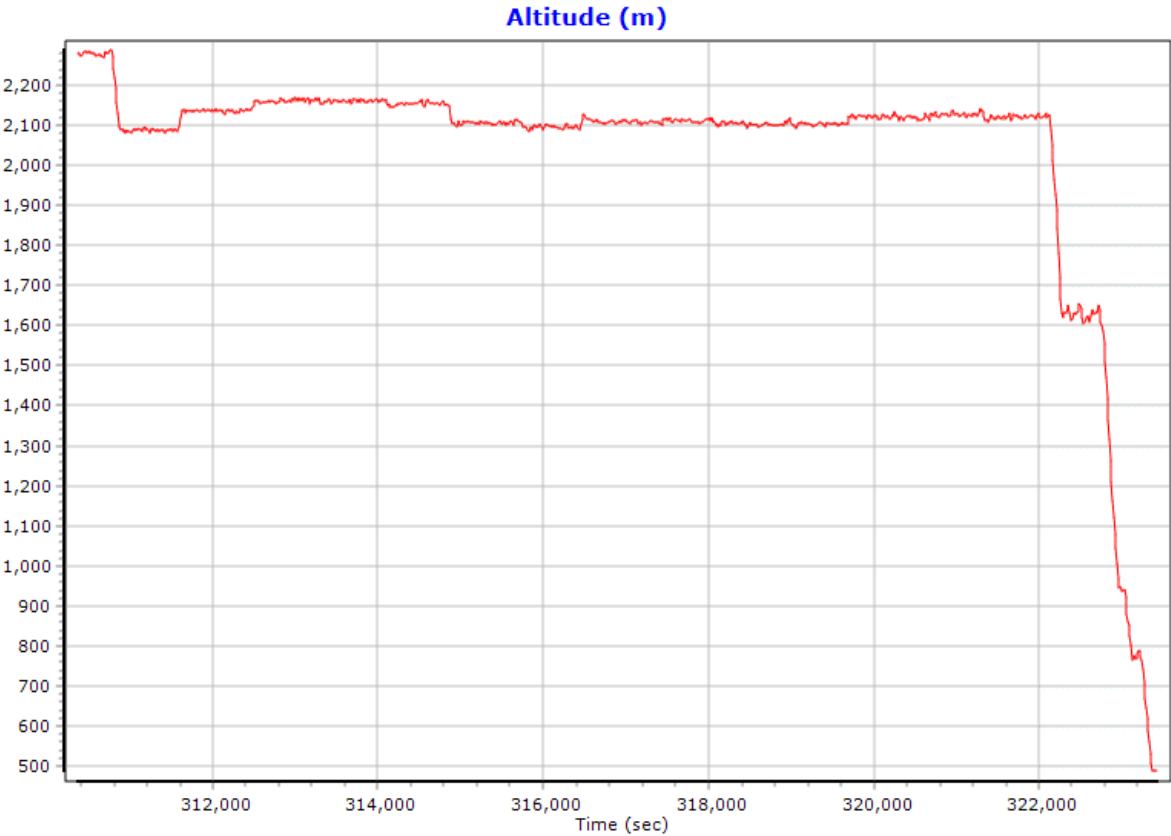
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	250340.000	259221.000	8881.000	End of file

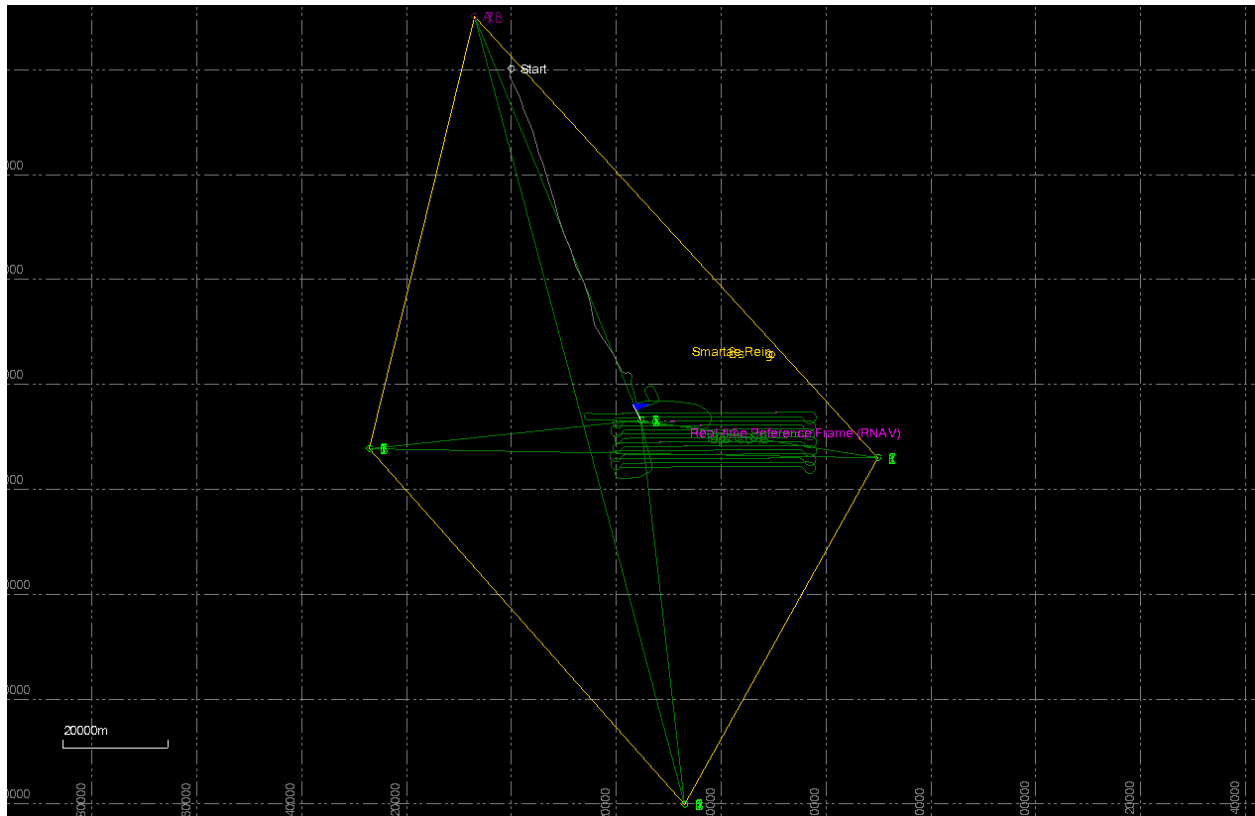
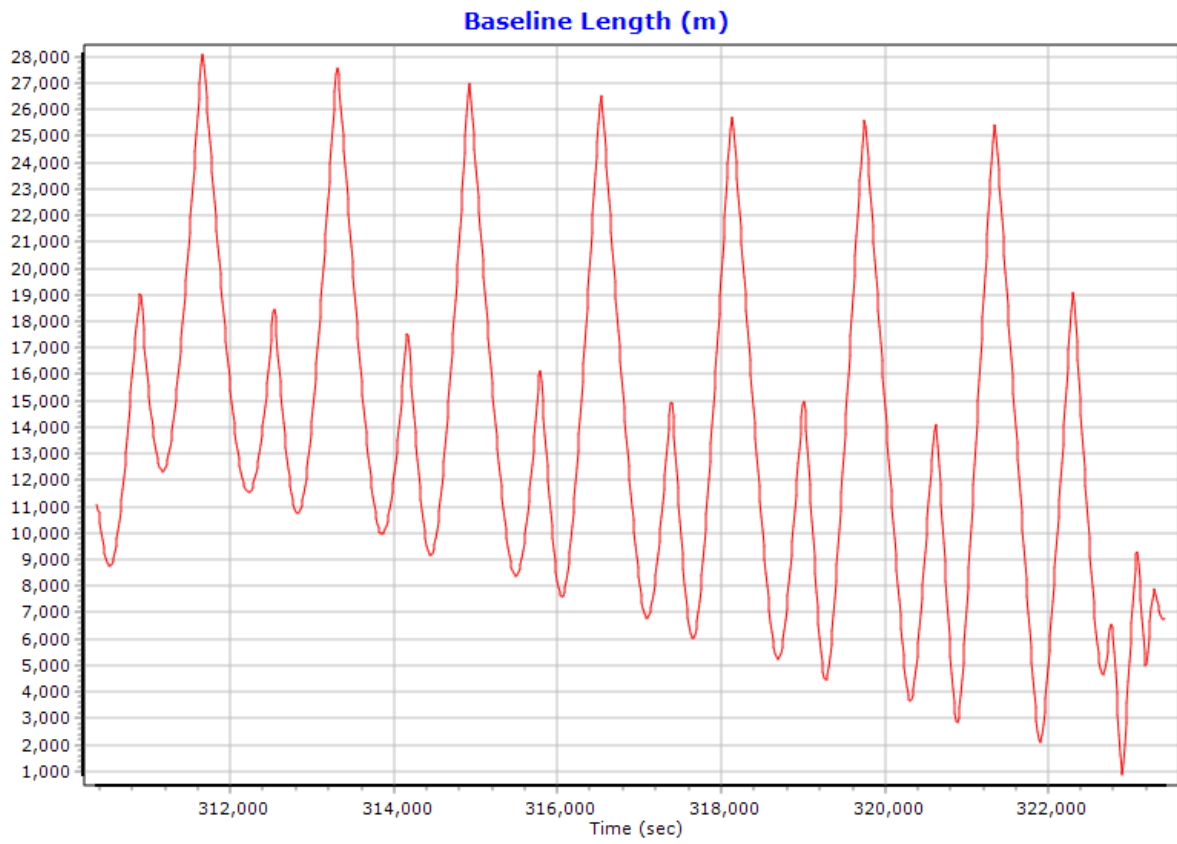
OK Cancel

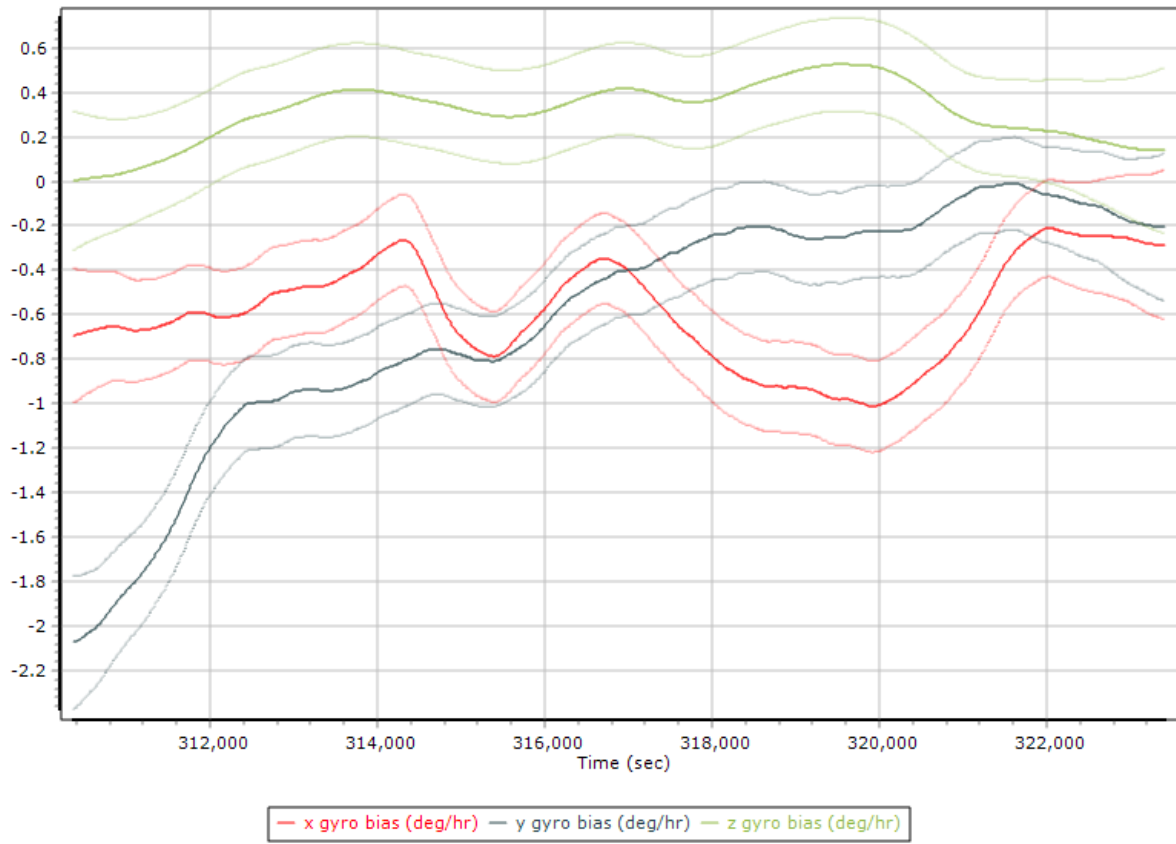
CAU18o8oA

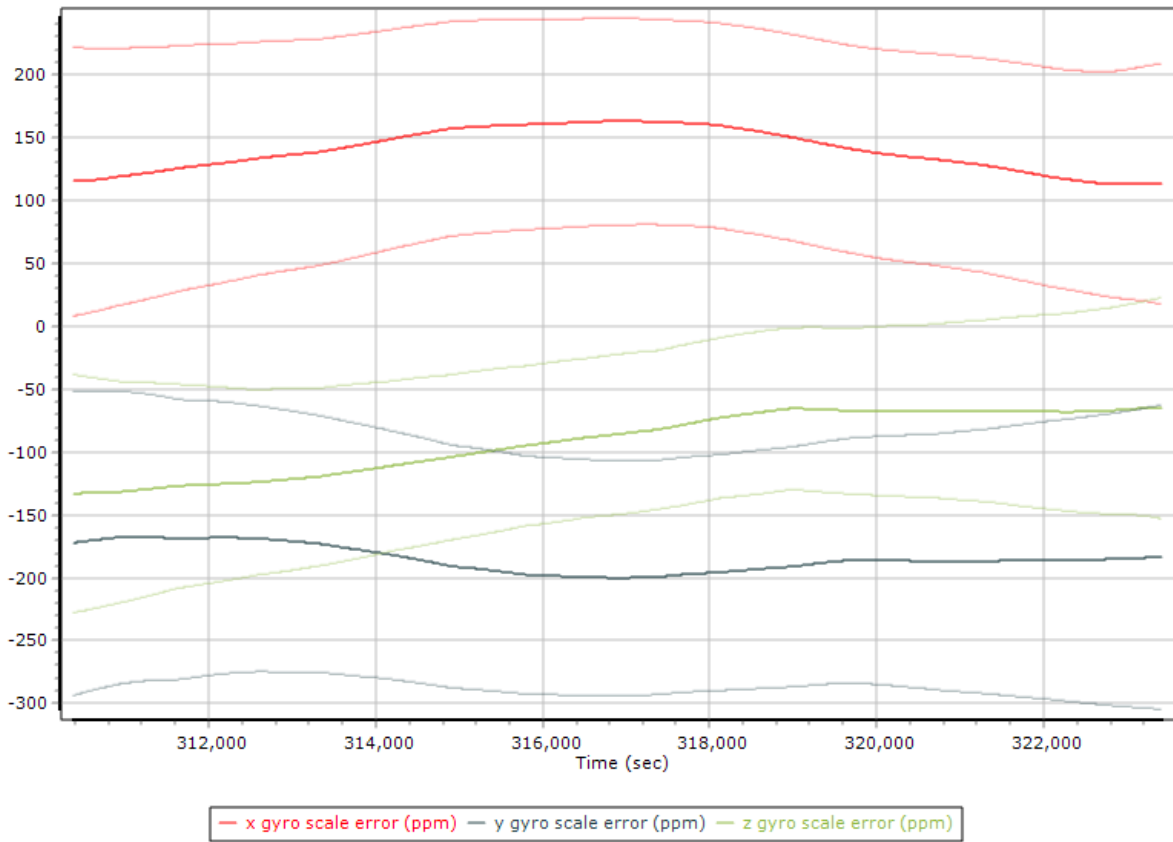












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- Export
- Camera
- LiDAR
- SAR

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

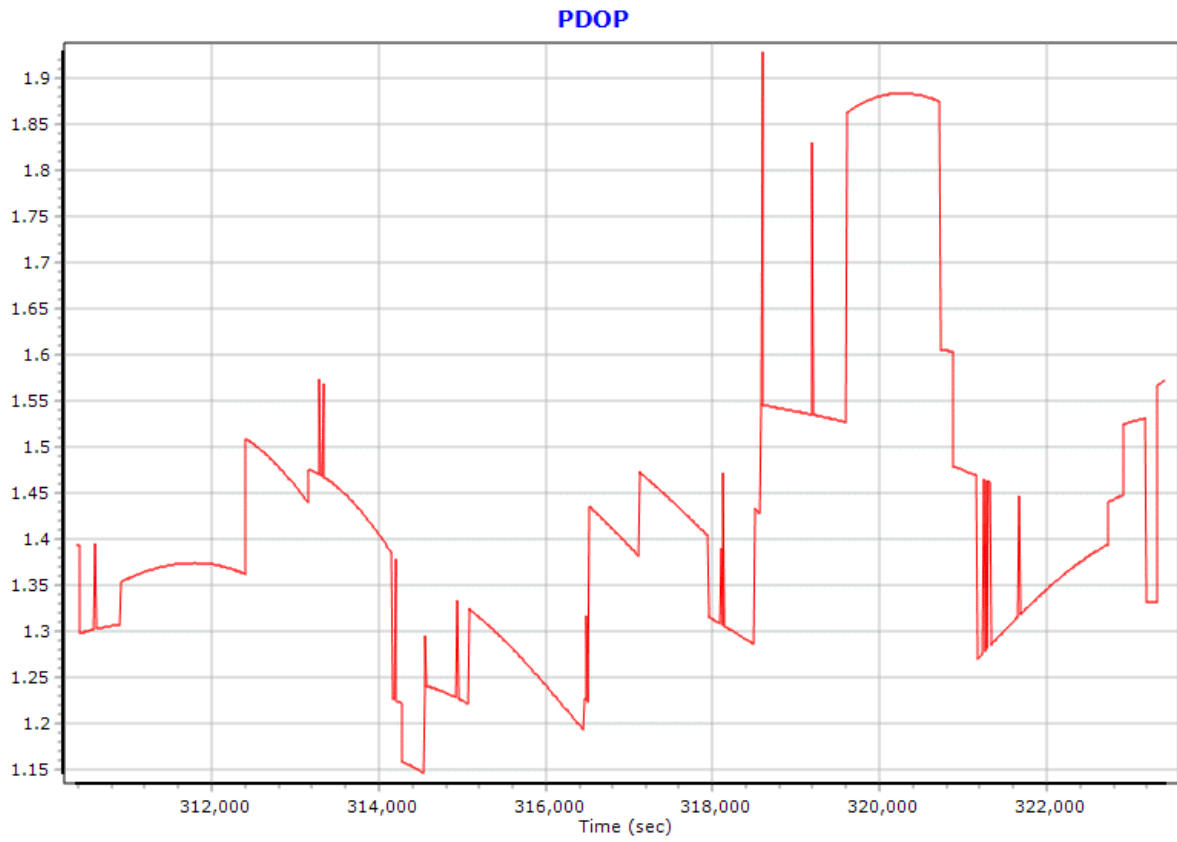
Aircraft to Reference Mounting Angles

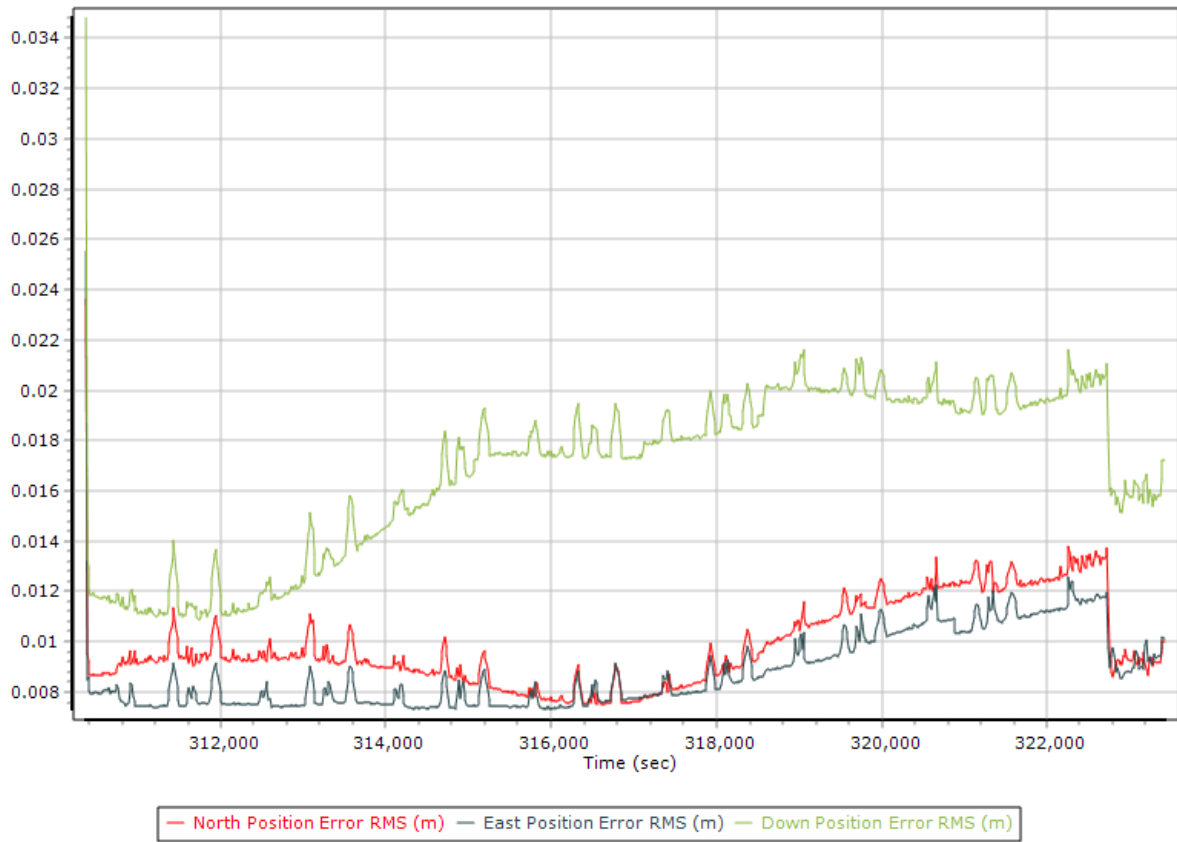
X:

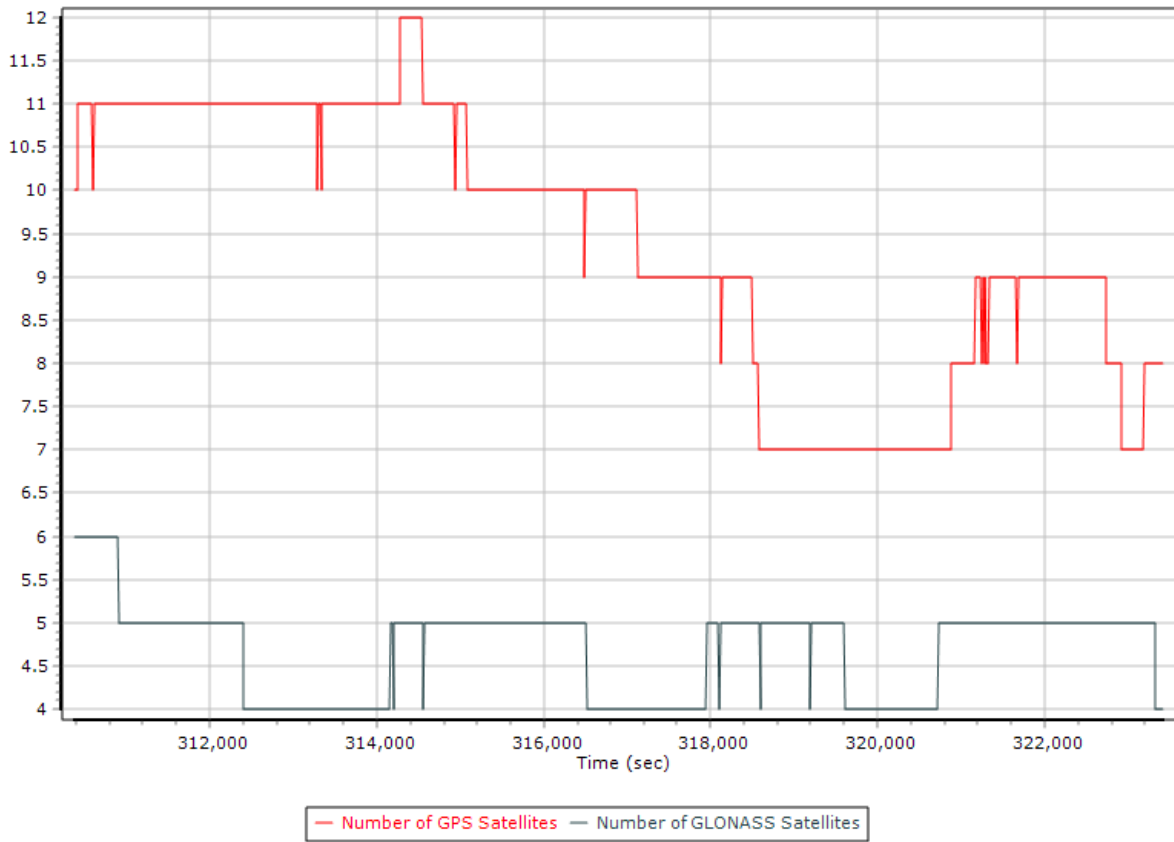
Y:

Z:

OK Cancel







Project Settings

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Disable Satellites

GPS | GLONASS | BEIDOU | QZSS

<input type="checkbox"/> PRN 1	<input type="checkbox"/> PRN 10	<input type="checkbox"/> PRN 19	<input type="checkbox"/> PRN 28
<input type="checkbox"/> PRN 2	<input type="checkbox"/> PRN 11	<input type="checkbox"/> PRN 20	<input type="checkbox"/> PRN 29
<input type="checkbox"/> PRN 3	<input type="checkbox"/> PRN 12	<input type="checkbox"/> PRN 21	<input type="checkbox"/> PRN 30
<input type="checkbox"/> PRN 4	<input type="checkbox"/> PRN 13	<input type="checkbox"/> PRN 22	<input type="checkbox"/> PRN 31
<input type="checkbox"/> PRN 5	<input type="checkbox"/> PRN 14	<input type="checkbox"/> PRN 23	<input type="checkbox"/> PRN 32
<input type="checkbox"/> PRN 6	<input type="checkbox"/> PRN 15	<input type="checkbox"/> PRN 24	
<input type="checkbox"/> PRN 7	<input type="checkbox"/> PRN 16	<input type="checkbox"/> PRN 25	
<input type="checkbox"/> PRN 8	<input type="checkbox"/> PRN 17	<input type="checkbox"/> PRN 26	
<input type="checkbox"/> PRN 9	<input type="checkbox"/> PRN 18	<input type="checkbox"/> PRN 27	

Elevation Mask Angle: 12.000 deg

Force GPS Only

OK Cancel



Project Settings

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- Camera
- LIDAR
- SAR

Timing

Start: 308346.000
 End: 323446.000

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

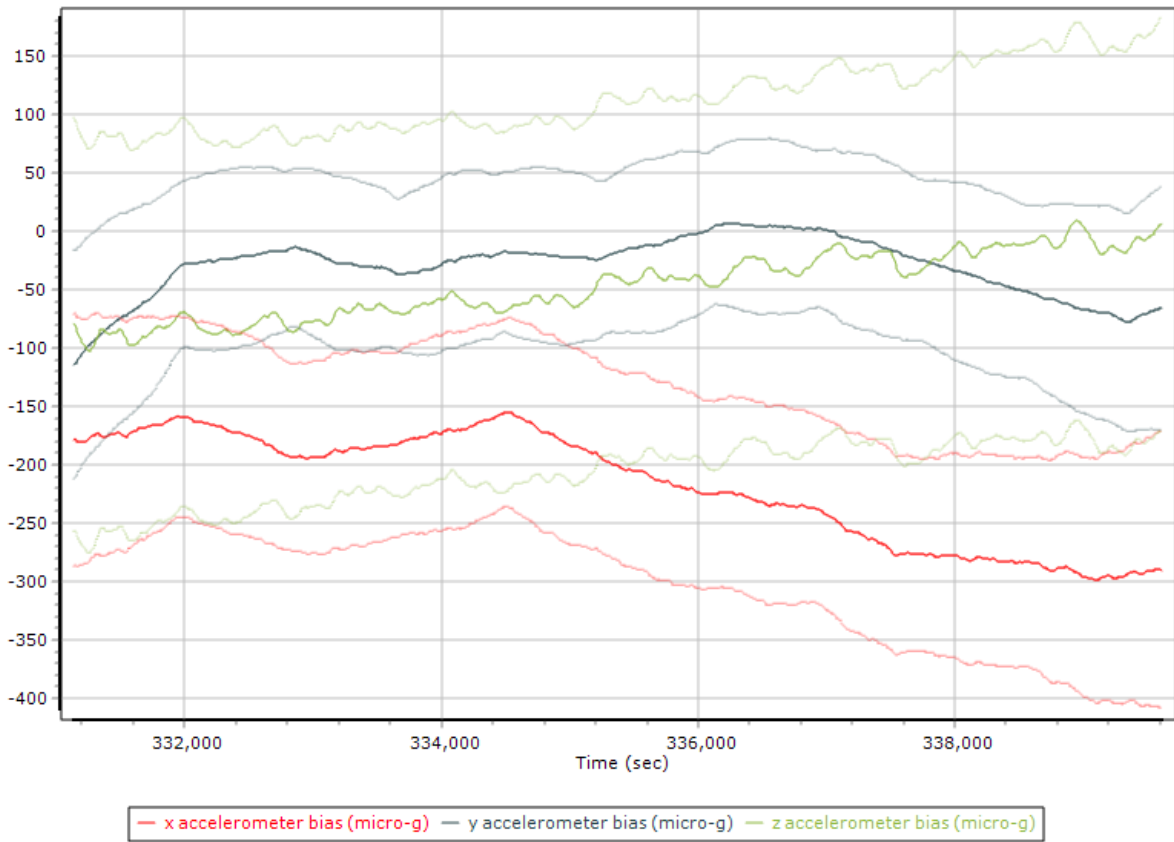
Processable Time Windows

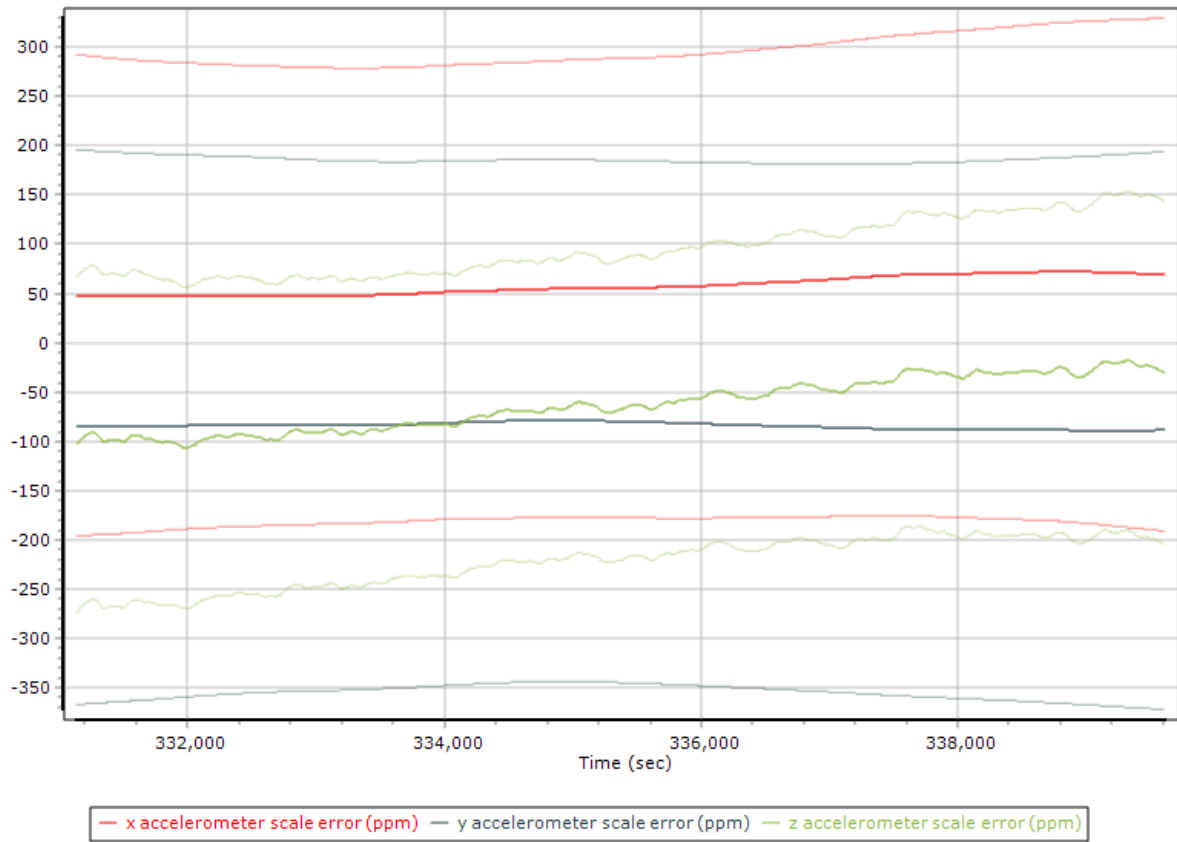
Start after launch Wait Time: 4.000 sec

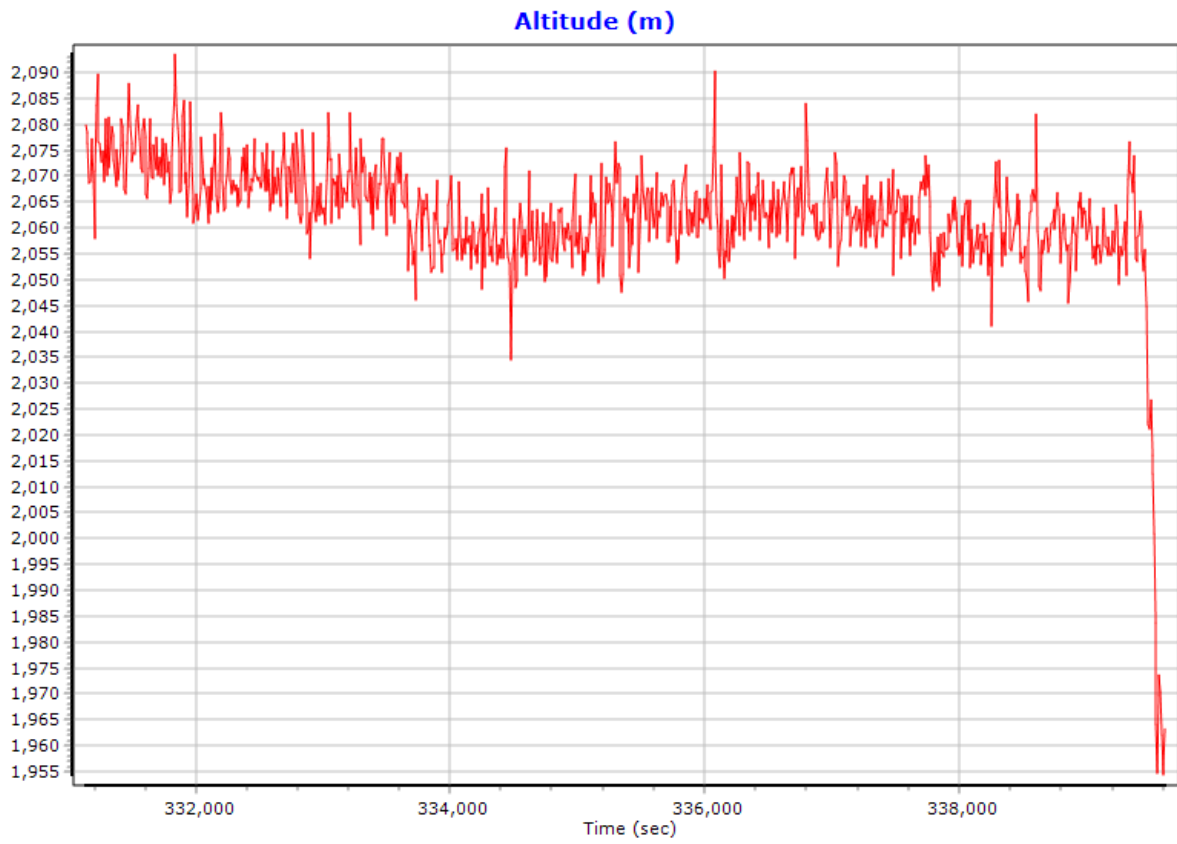
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	308346.000	323446.000	15100.000	End of file

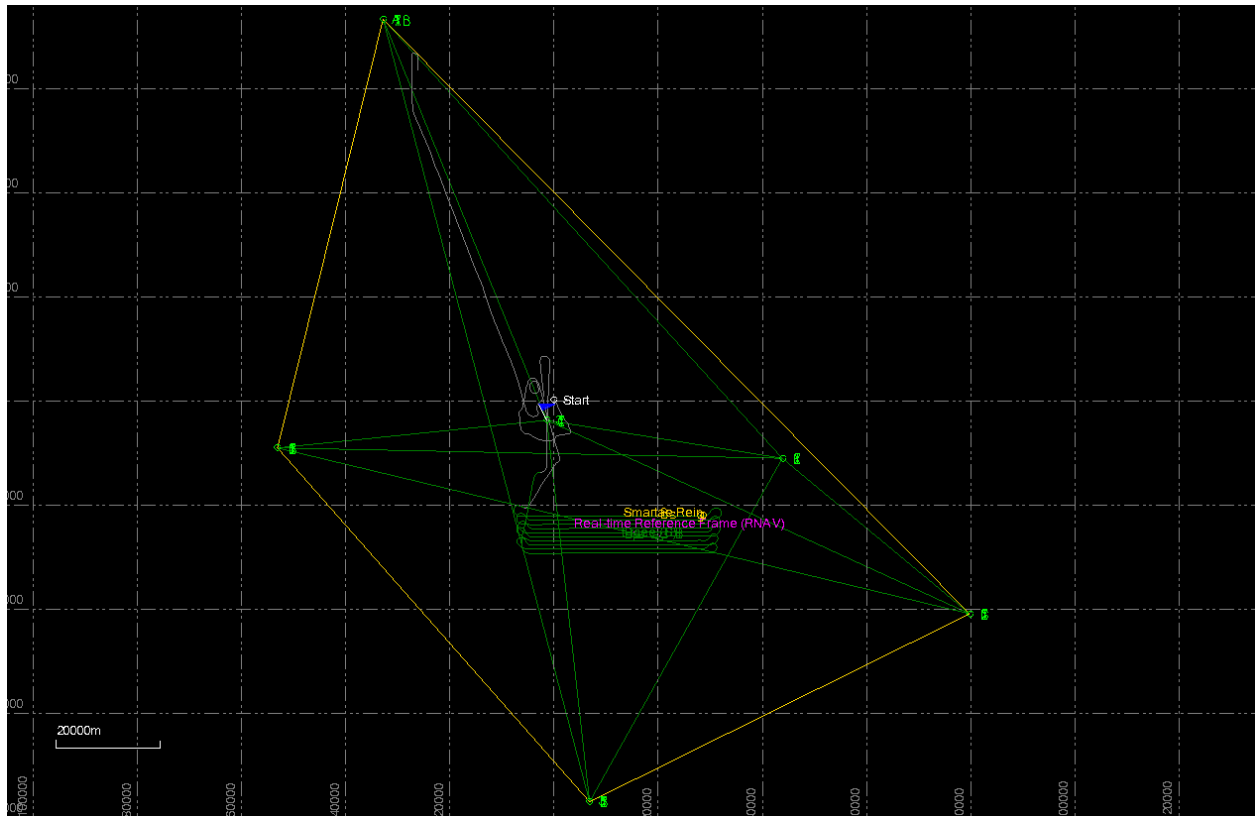
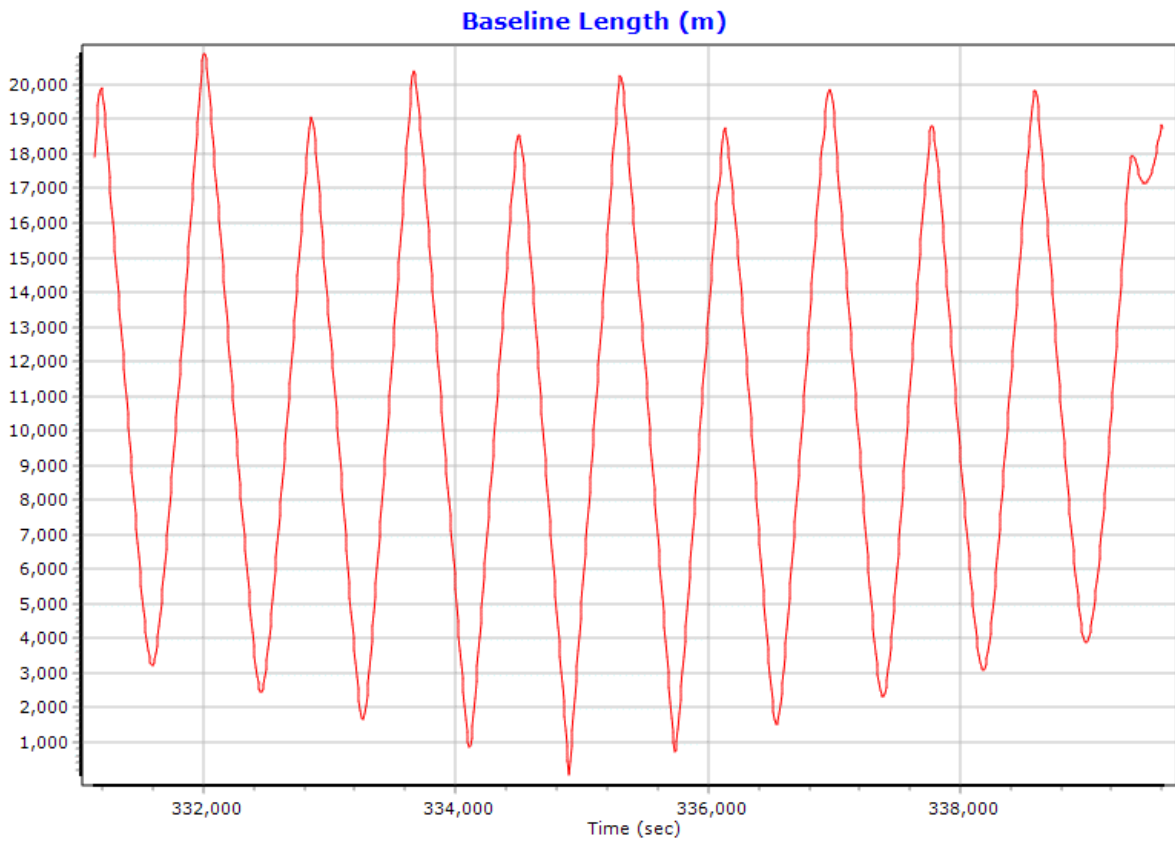
OK Cancel

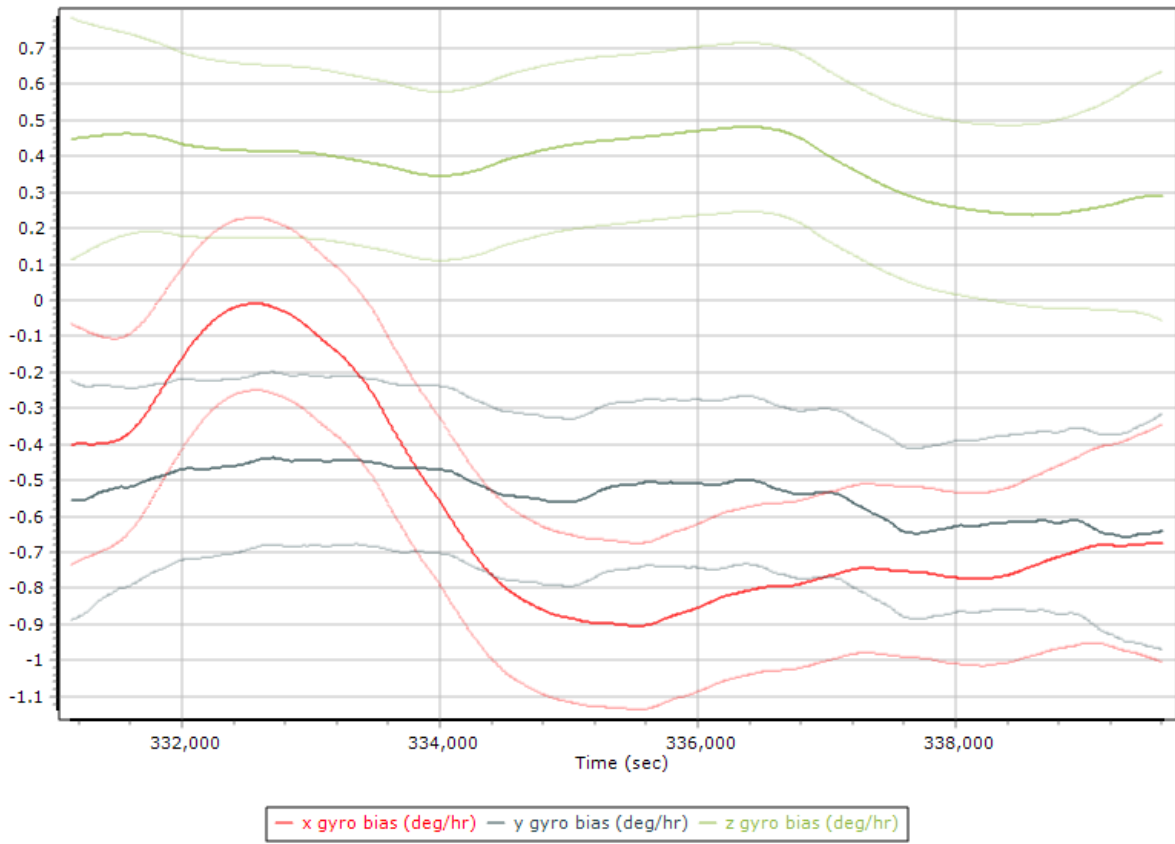
CAU18o8oB

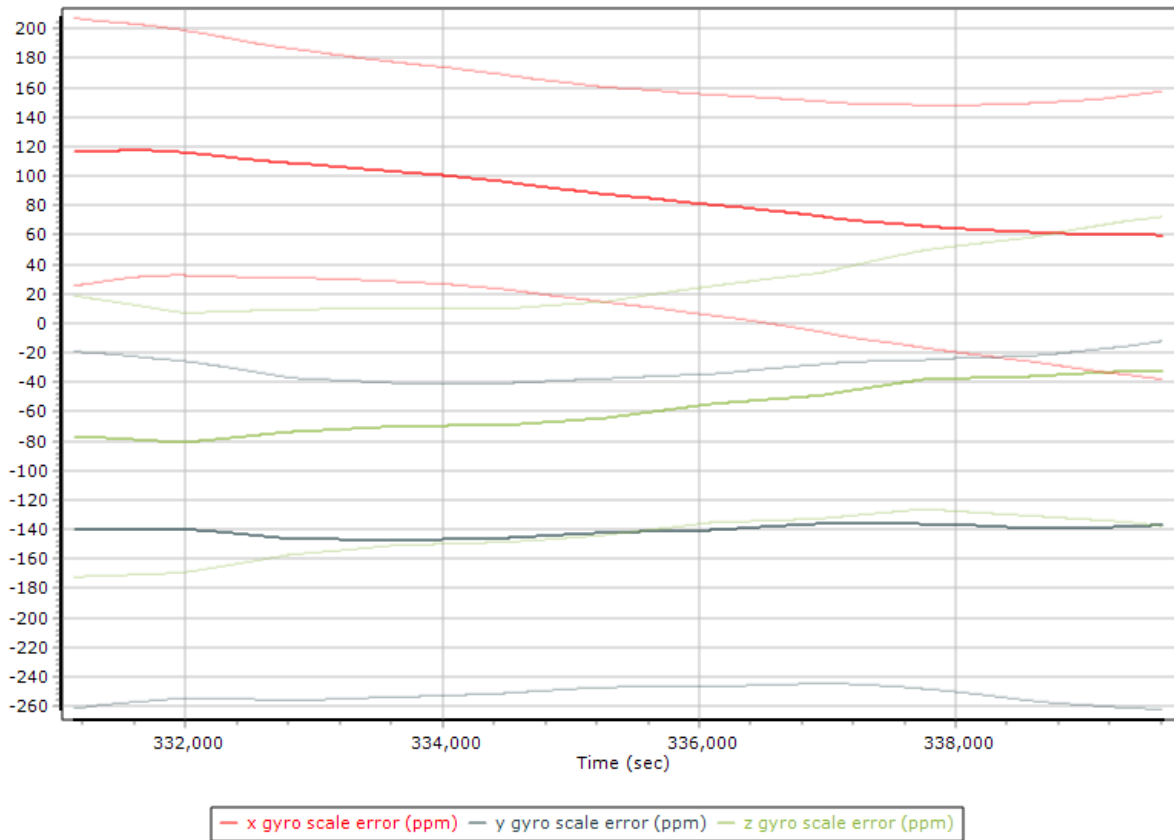












Project Settings

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- Export
- Camera
- LiDAR
- SAR

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

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

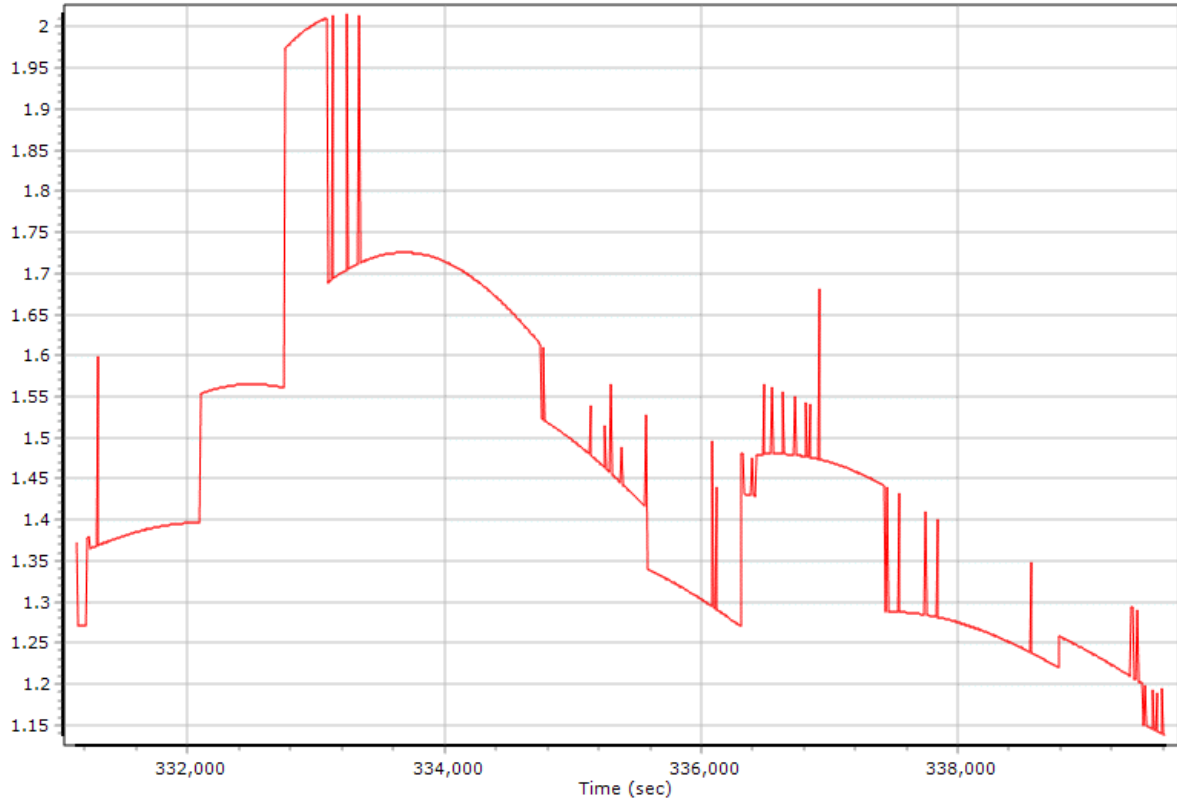
Aircraft to Reference Mounting Angles

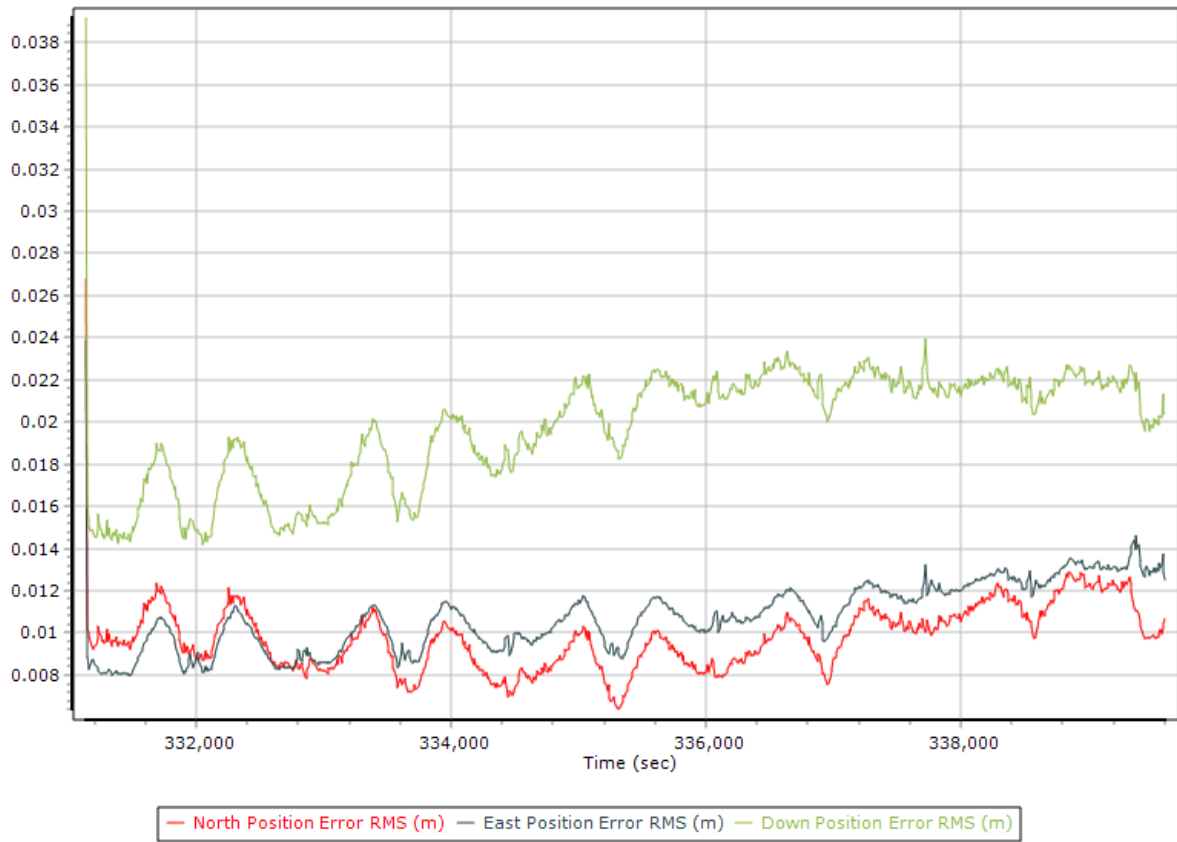
X:

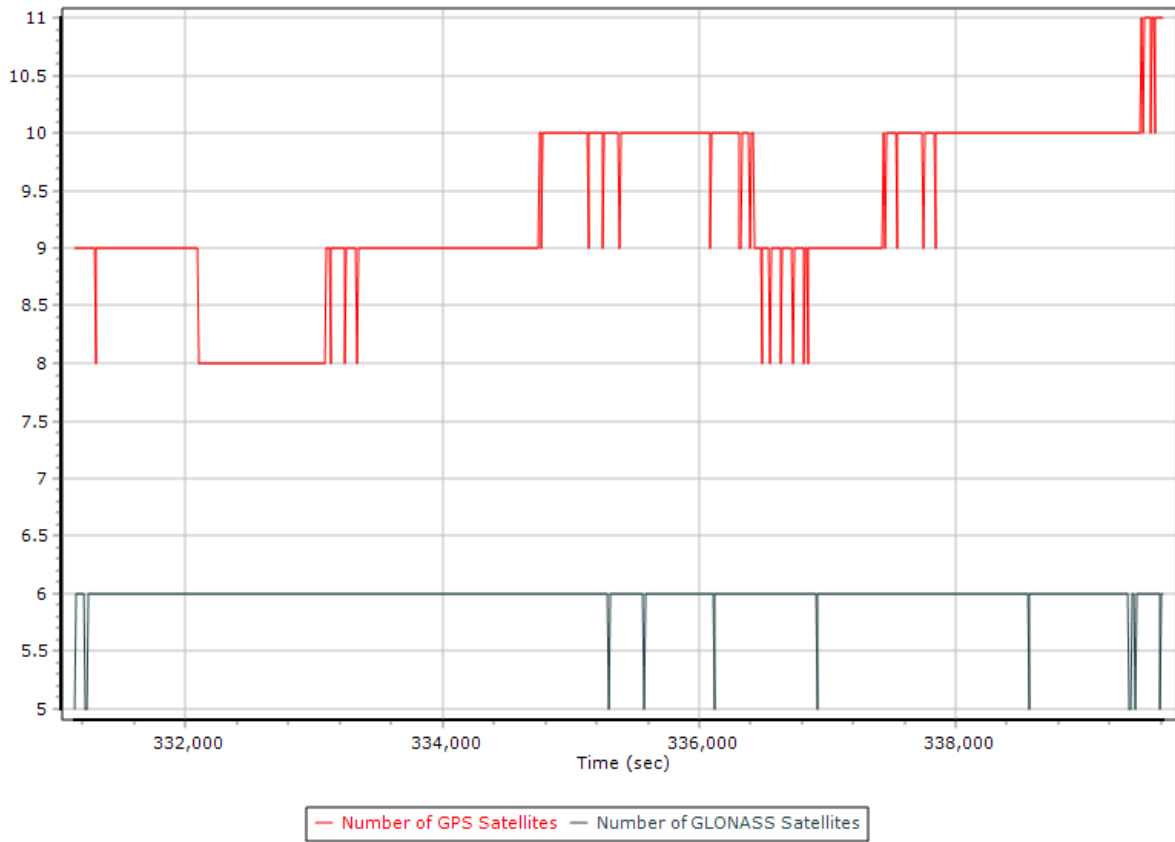
Y:

Z:

PDOP







Project Settings

- General Information
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- Satellite Selection**
- GNSS-Inertial Processor
- Export
- Camera
- LIDAR
- SAR

Disable Satellites

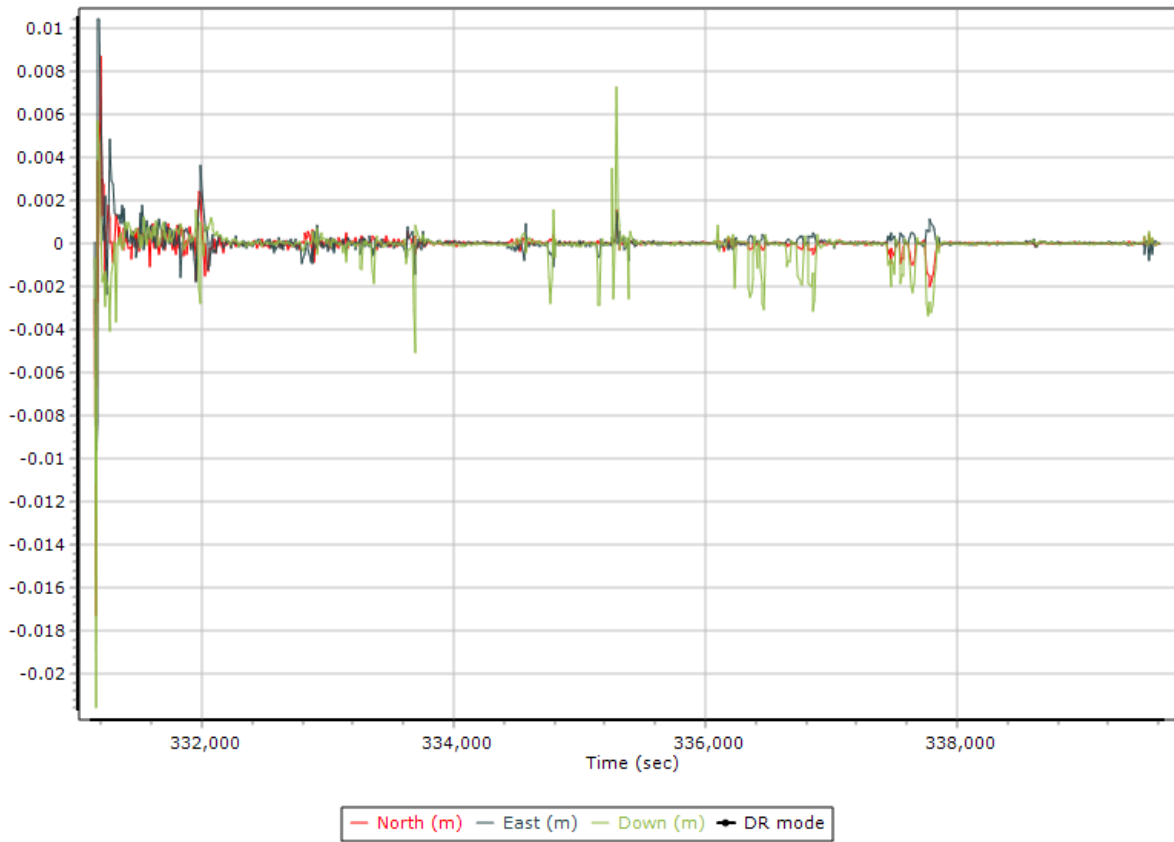
GPS | **GLONASS** | BEIDOU | QZSS

<input type="checkbox"/> PRN 1	<input type="checkbox"/> PRN 10	<input type="checkbox"/> PRN 19	<input type="checkbox"/> PRN 28
<input type="checkbox"/> PRN 2	<input type="checkbox"/> PRN 11	<input type="checkbox"/> PRN 20	<input type="checkbox"/> PRN 29
<input type="checkbox"/> PRN 3	<input type="checkbox"/> PRN 12	<input type="checkbox"/> PRN 21	<input type="checkbox"/> PRN 30
<input type="checkbox"/> PRN 4	<input type="checkbox"/> PRN 13	<input type="checkbox"/> PRN 22	<input type="checkbox"/> PRN 31
<input type="checkbox"/> PRN 5	<input type="checkbox"/> PRN 14	<input type="checkbox"/> PRN 23	<input type="checkbox"/> PRN 32
<input type="checkbox"/> PRN 6	<input type="checkbox"/> PRN 15	<input type="checkbox"/> PRN 24	
<input type="checkbox"/> PRN 7	<input type="checkbox"/> PRN 16	<input type="checkbox"/> PRN 25	
<input type="checkbox"/> PRN 8	<input type="checkbox"/> PRN 17	<input type="checkbox"/> PRN 26	
<input type="checkbox"/> PRN 9	<input type="checkbox"/> PRN 18	<input type="checkbox"/> PRN 27	

Elevation Mask Angle:

Force GPS Only

OK Cancel



Project Settings [X]

- General Information
- Units
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 - Timing**
 - Algorithms
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- Export
- Camera
- LiDAR
- SAR

Timing

Start: 329337.000
 End: 341729.000
 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

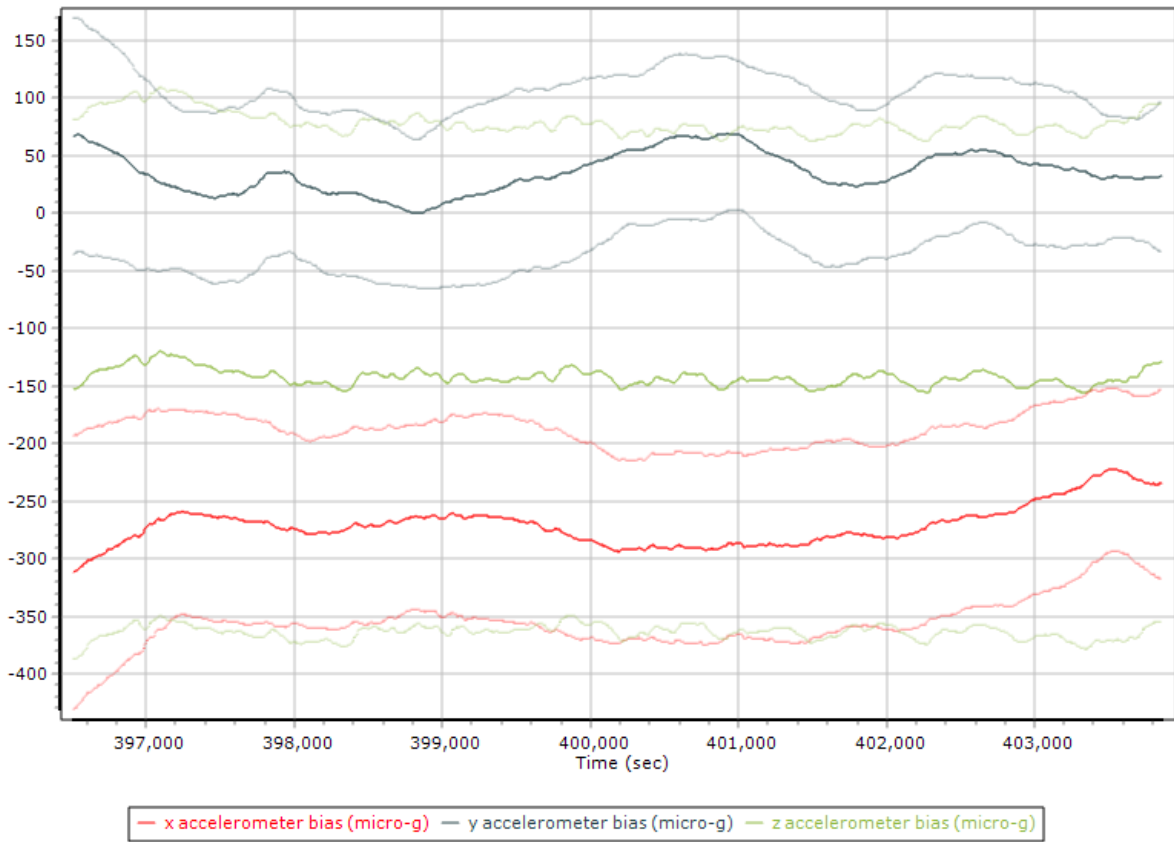
Processable Time Windows

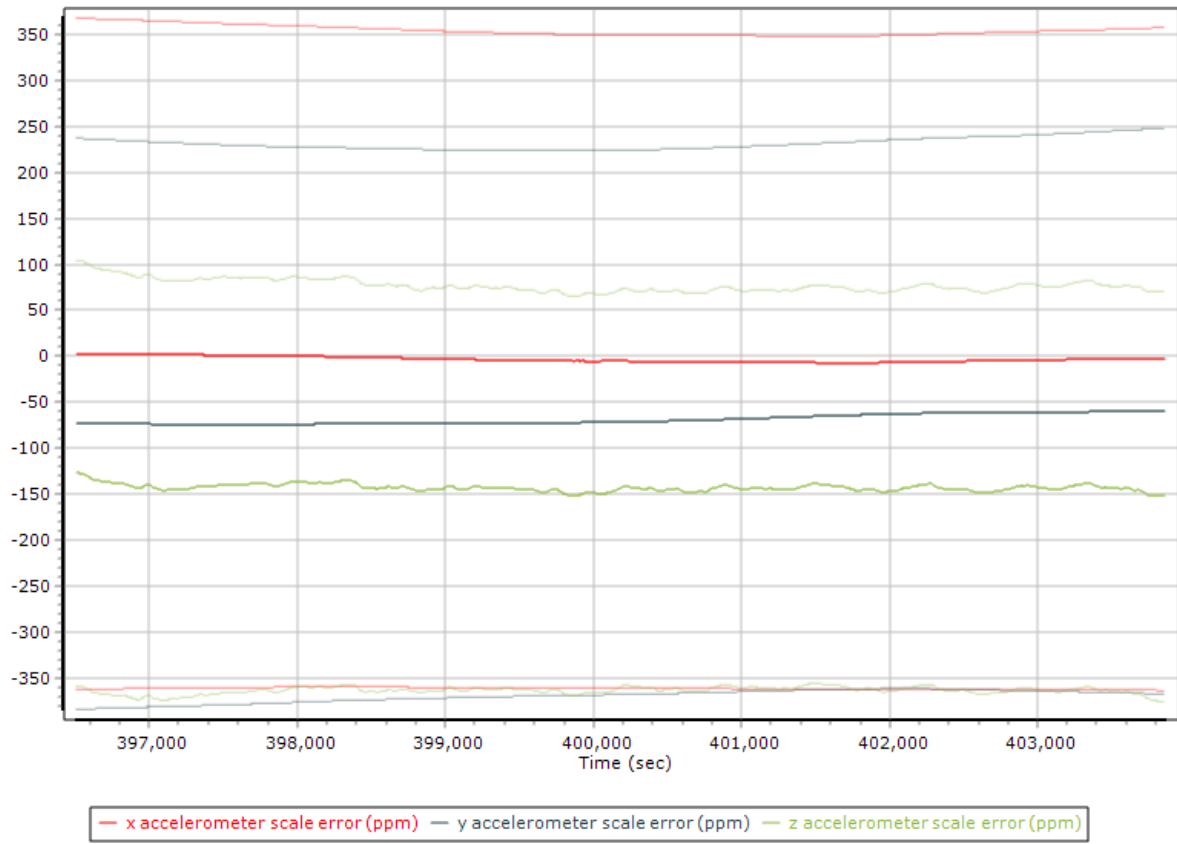
Start after launch Wait Time: 4.000 sec

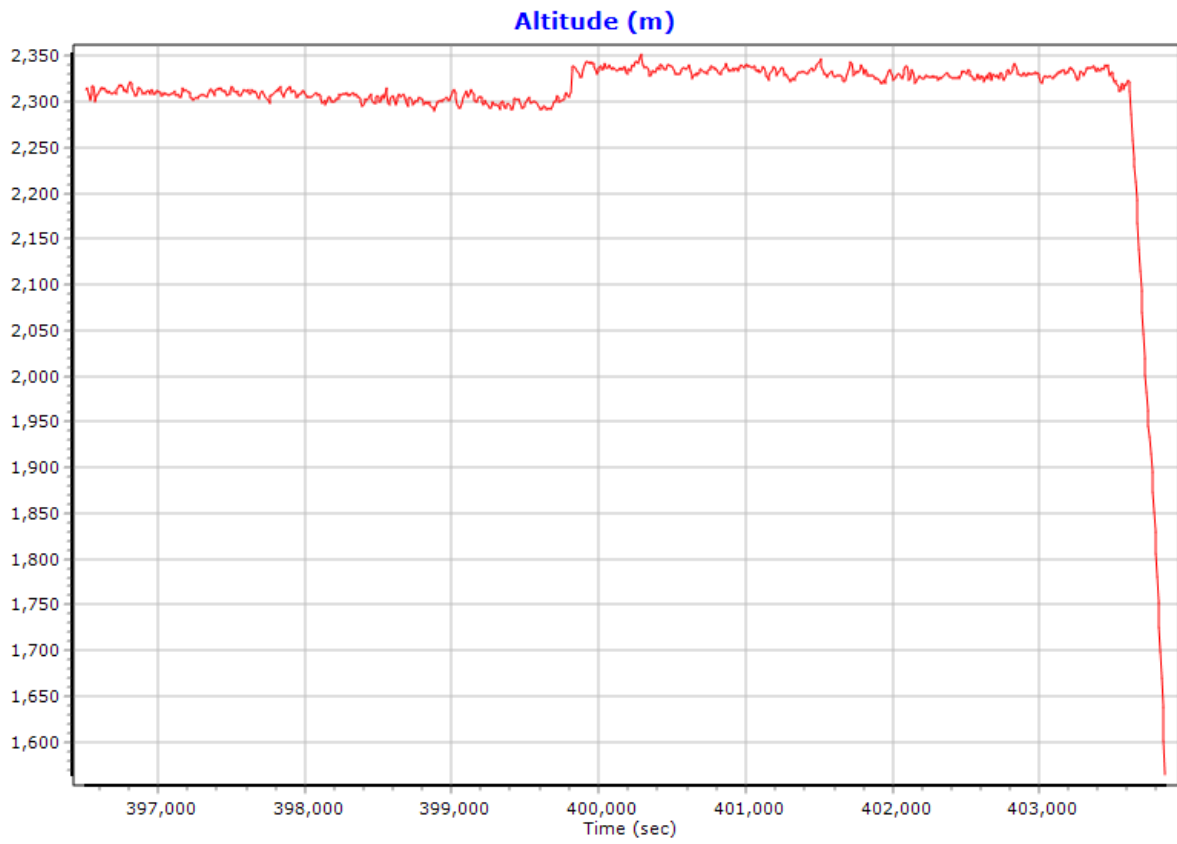
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	329337.000	341729.000	12392.000	End of file

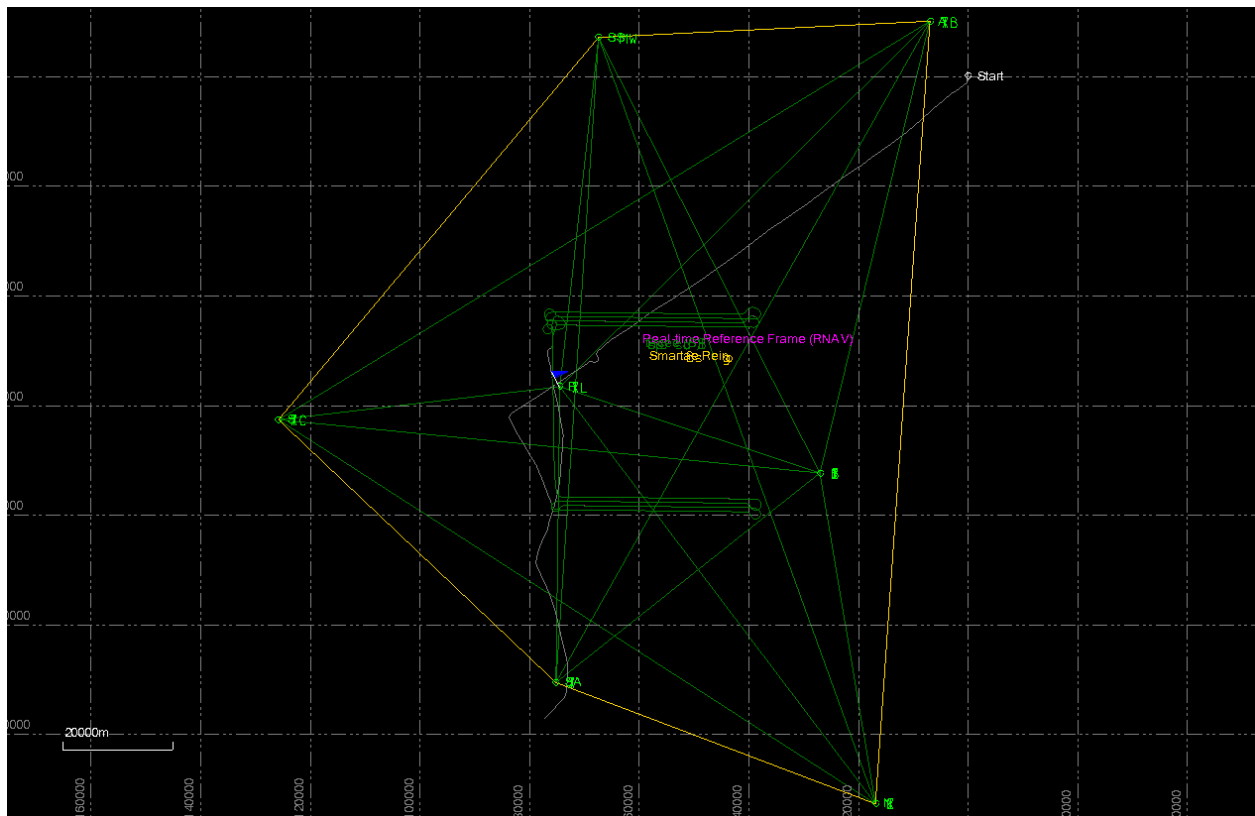
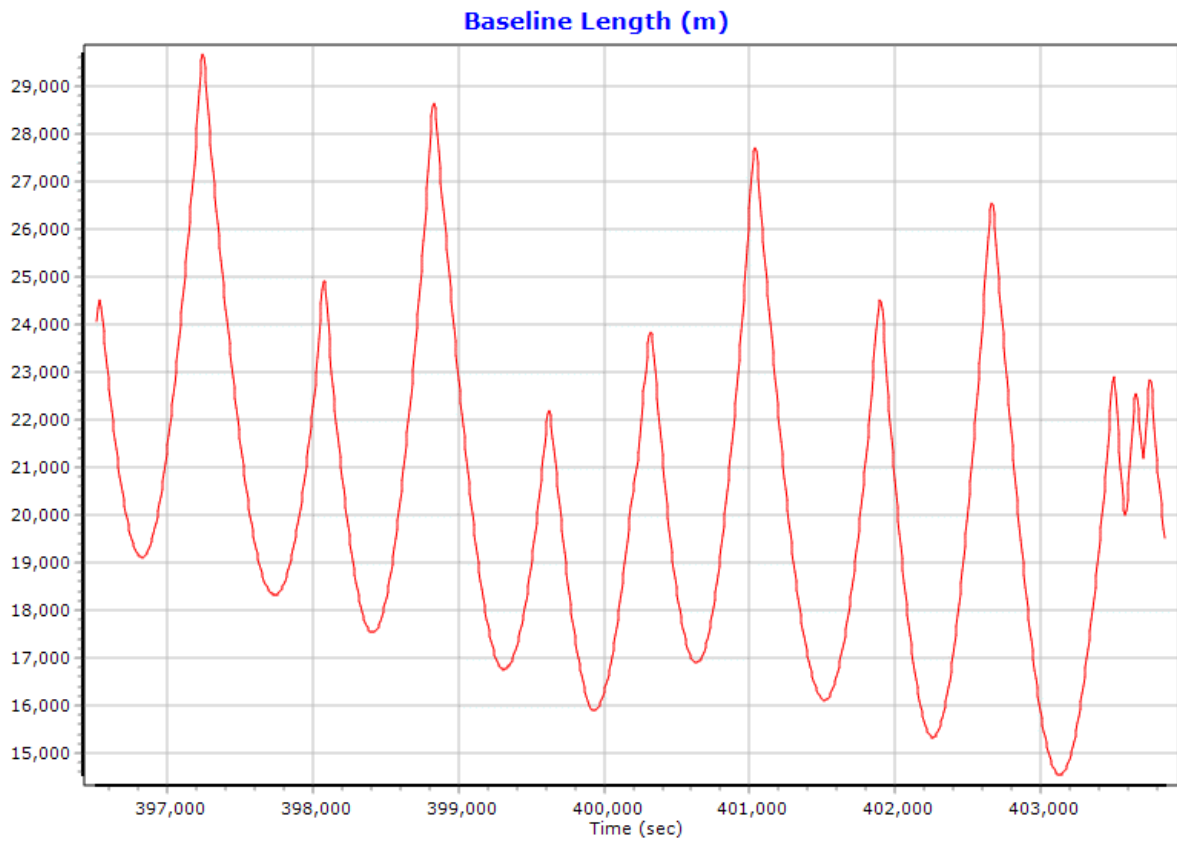
OK Cancel

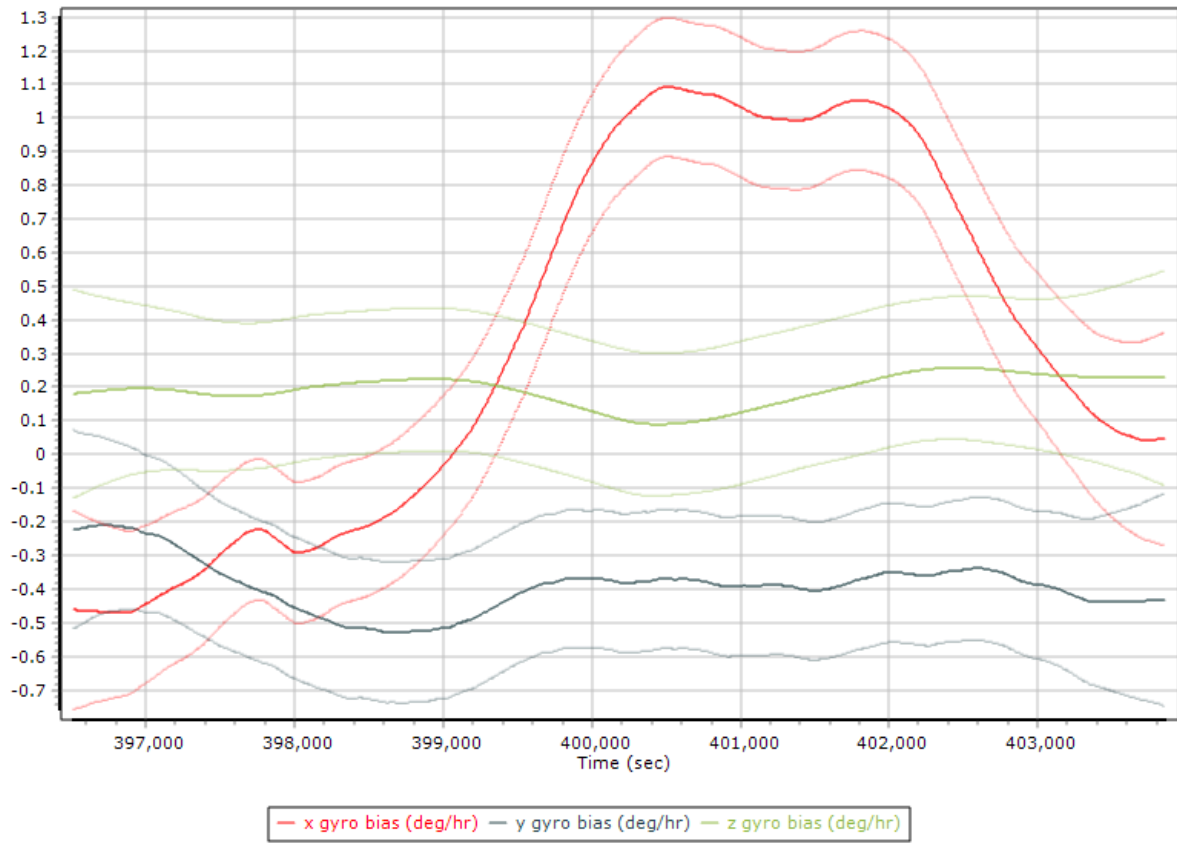
CAU18081A

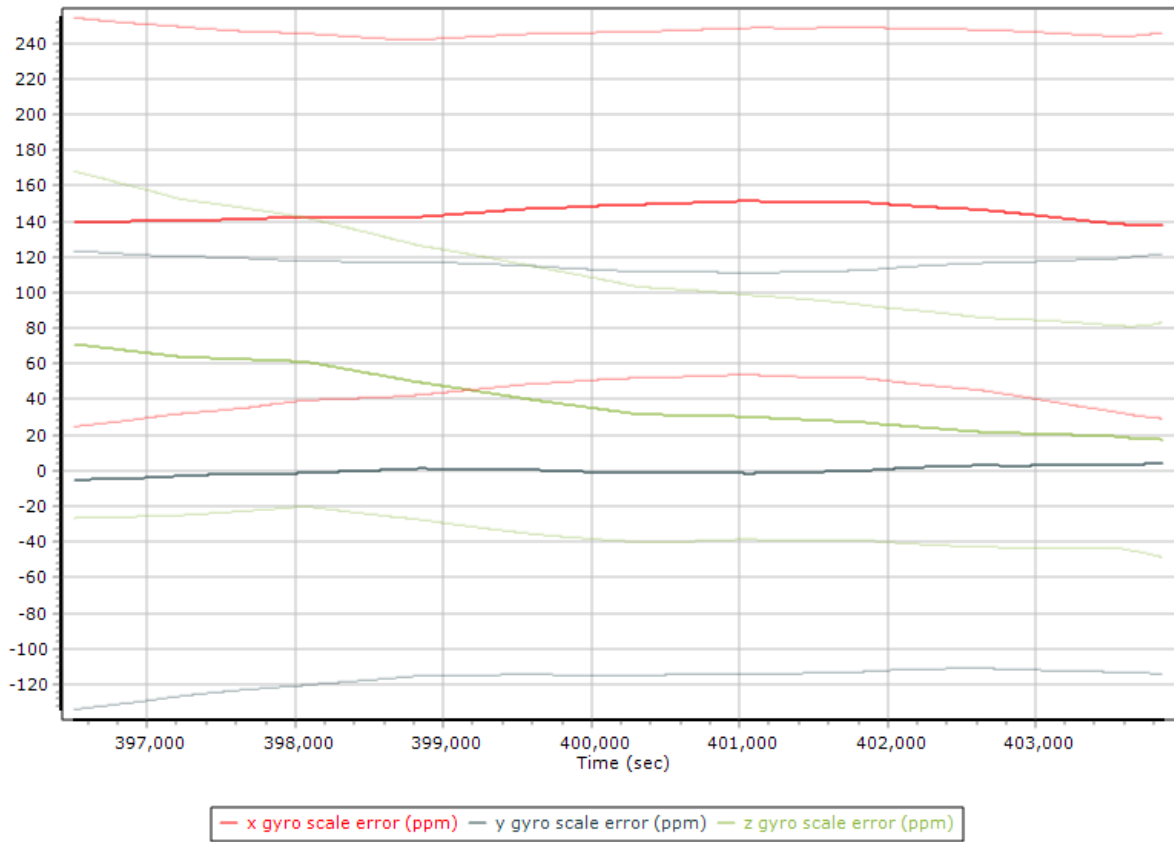












Project Settings [X]

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation: [▼]

<3cm 10cm 50cm 1m 10m

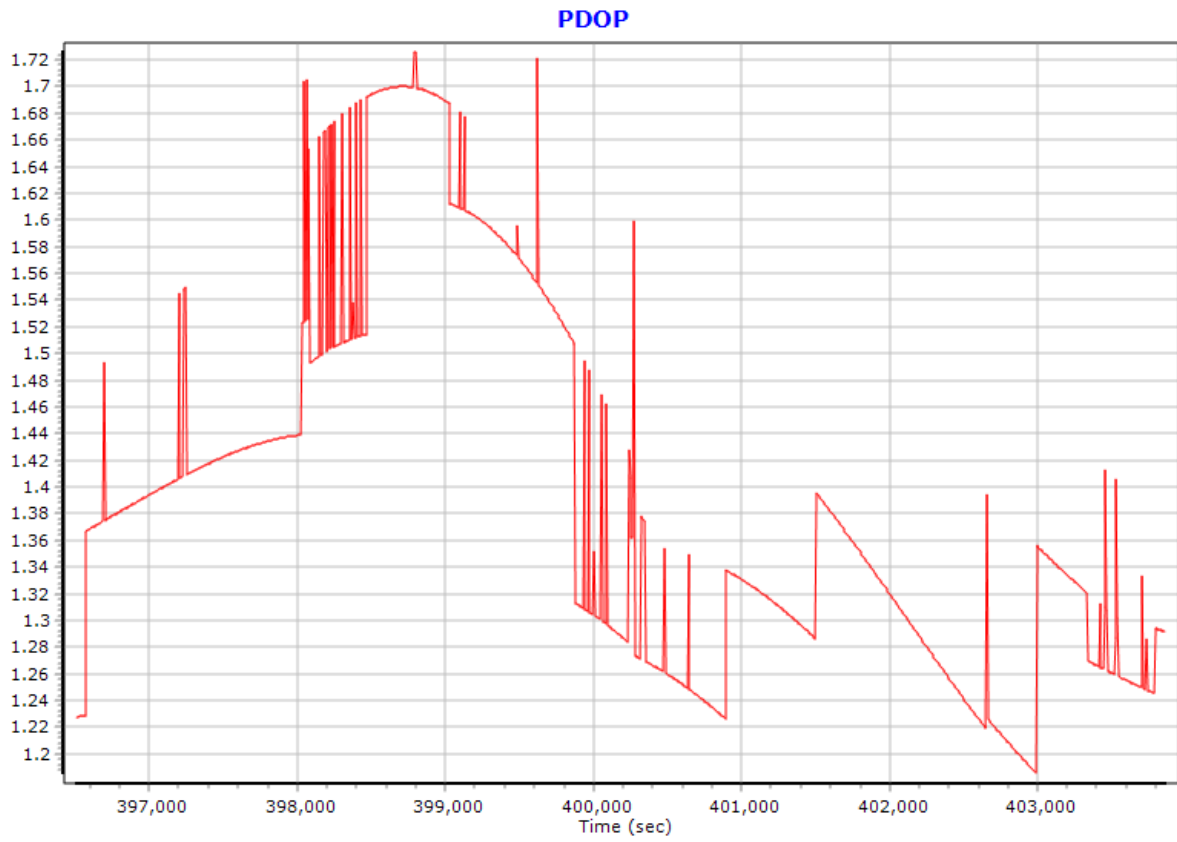
Aircraft to Reference Mounting Angles

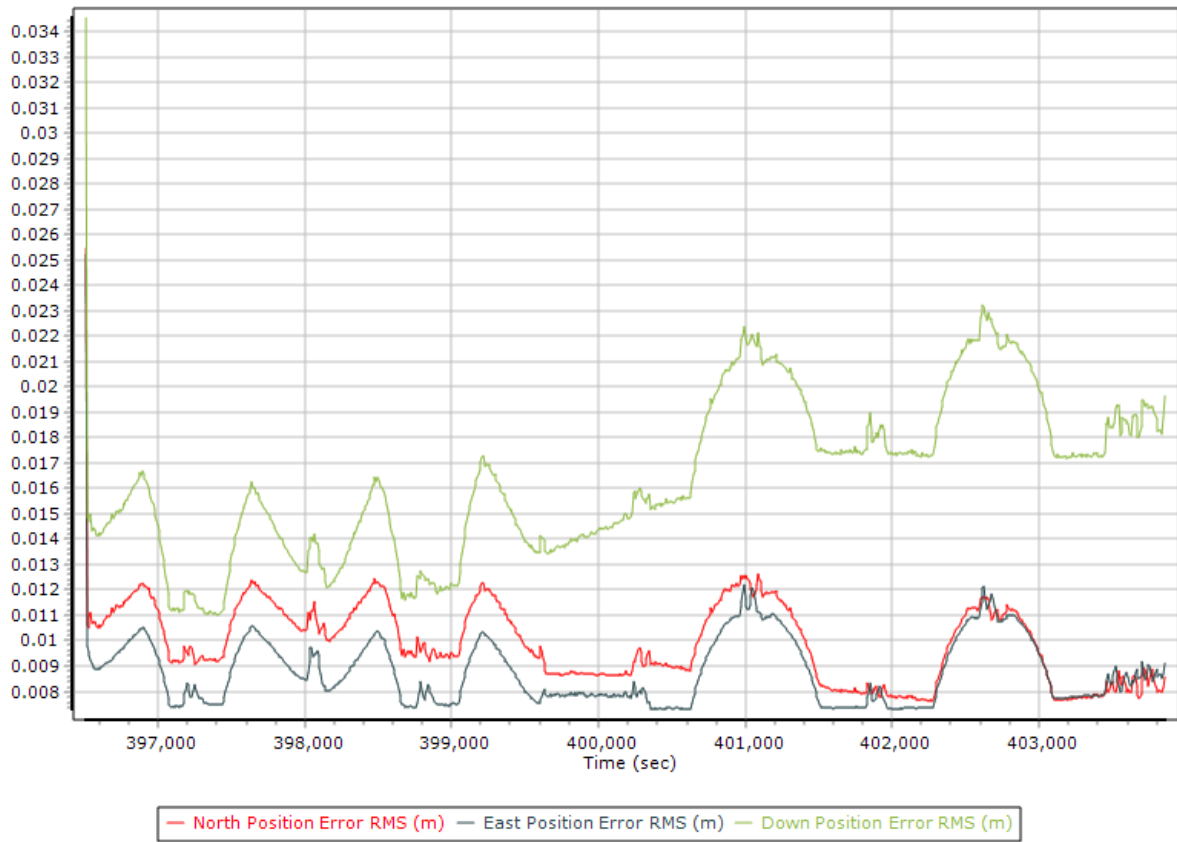
X:

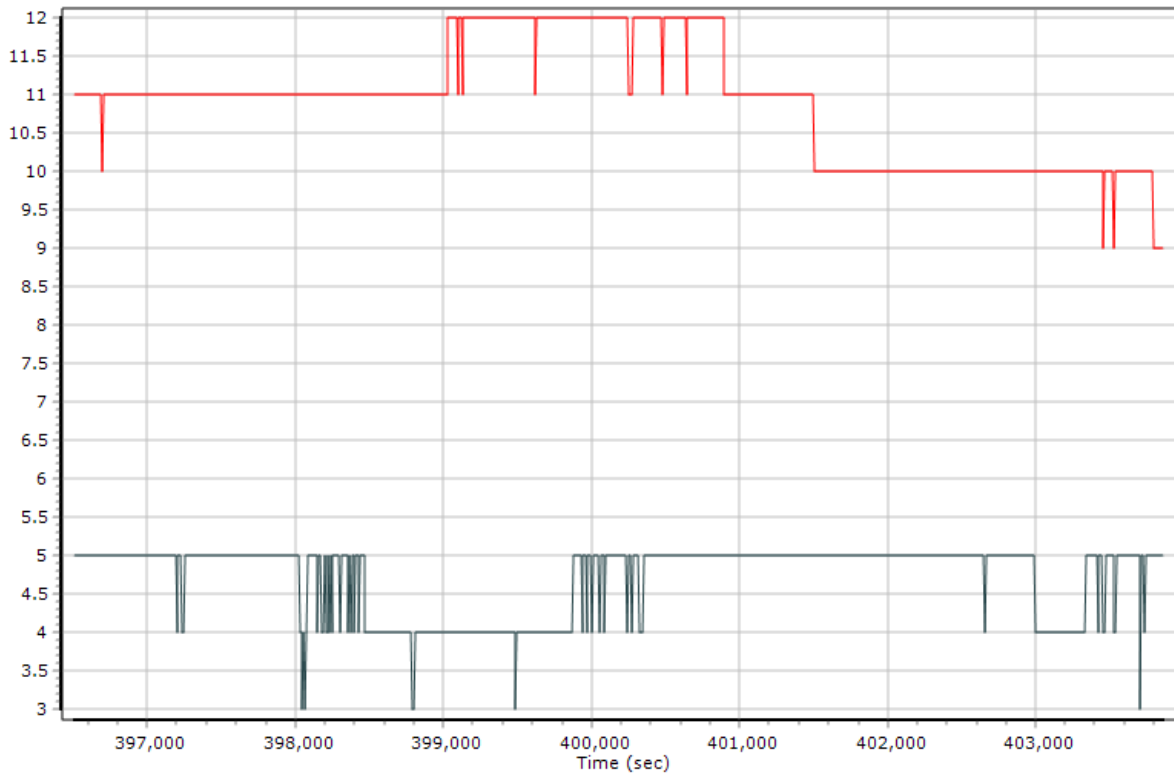
Y:

Z:

OK Cancel







— Number of GPS Satellites — Number of GLONASS Satellites

Project Settings ✕

- General Information
- Units
- View
- Rover Import
- Satellite Selection**
- GNSS-Inertial Processor
- Export
- Camera
- LiDAR
- SAR

Disable Satellites

GPS | **GLONASS** | BEIDOU | QZSS

<input type="checkbox"/> PRN 1	<input type="checkbox"/> PRN 10	<input type="checkbox"/> PRN 19	<input type="checkbox"/> PRN 28
<input type="checkbox"/> PRN 2	<input type="checkbox"/> PRN 11	<input type="checkbox"/> PRN 20	<input type="checkbox"/> PRN 29
<input type="checkbox"/> PRN 3	<input type="checkbox"/> PRN 12	<input type="checkbox"/> PRN 21	<input type="checkbox"/> PRN 30
<input type="checkbox"/> PRN 4	<input type="checkbox"/> PRN 13	<input type="checkbox"/> PRN 22	<input type="checkbox"/> PRN 31
<input type="checkbox"/> PRN 5	<input type="checkbox"/> PRN 14	<input type="checkbox"/> PRN 23	<input type="checkbox"/> PRN 32
<input type="checkbox"/> PRN 6	<input type="checkbox"/> PRN 15	<input type="checkbox"/> PRN 24	
<input type="checkbox"/> PRN 7	<input type="checkbox"/> PRN 16	<input type="checkbox"/> PRN 25	
<input type="checkbox"/> PRN 8	<input type="checkbox"/> PRN 17	<input type="checkbox"/> PRN 26	
<input type="checkbox"/> PRN 9	<input type="checkbox"/> PRN 18	<input type="checkbox"/> PRN 27	

Elevation Mask Angle

Force GPS Only



Project Settings [X]

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

Timing

Start: 392789.000
 End: 405696.000
 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

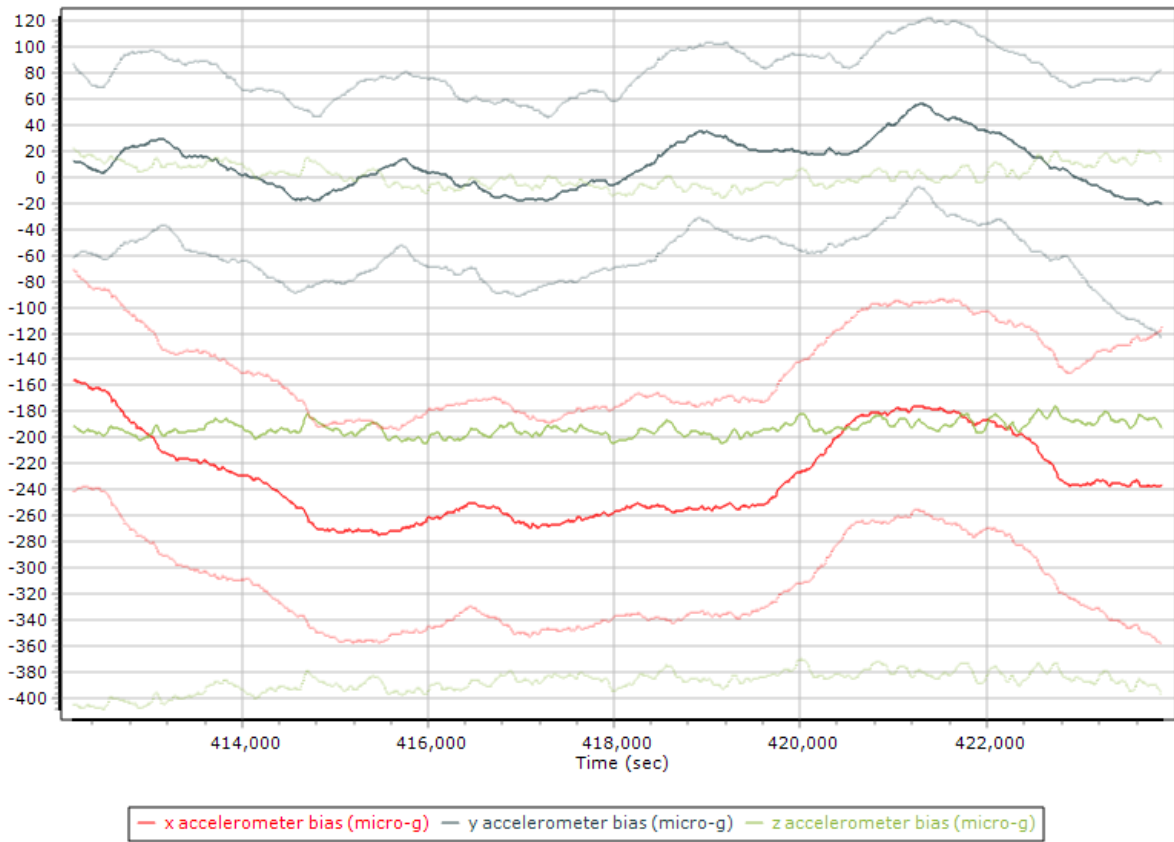
Processable Time Windows

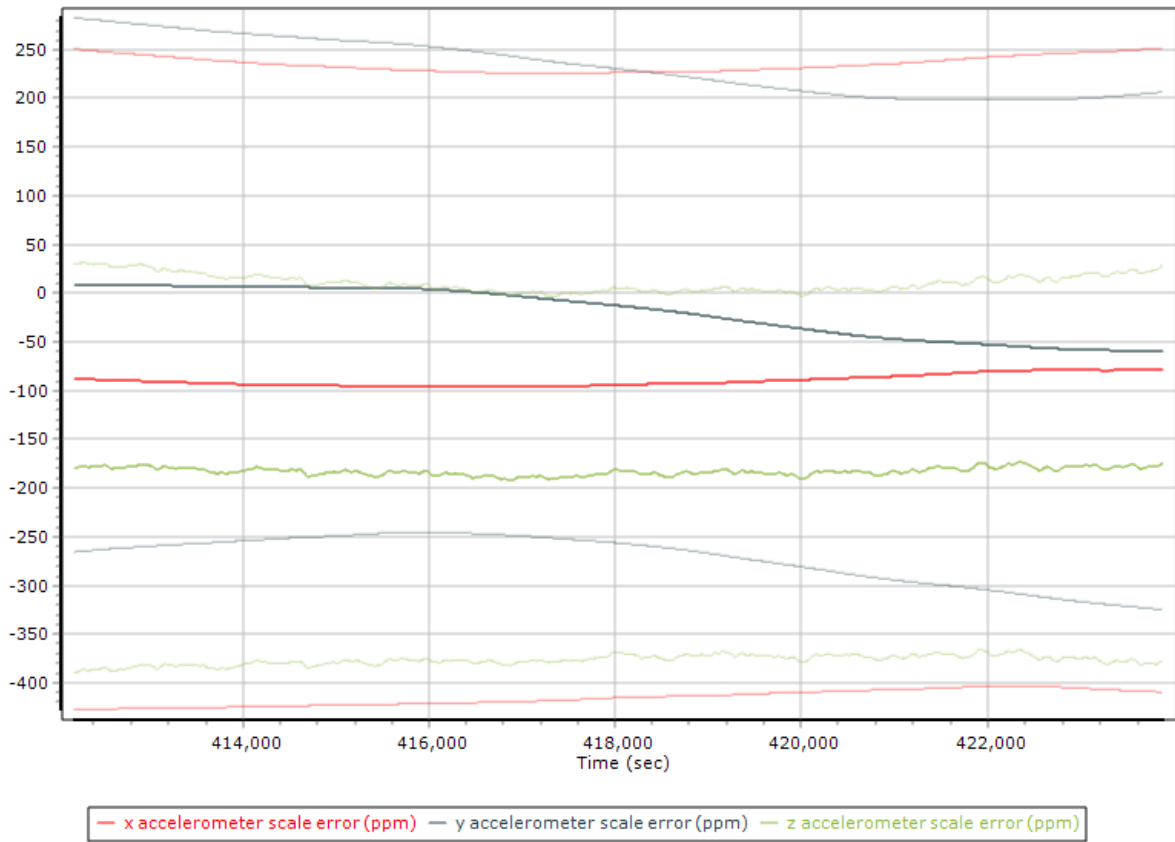
Start after launch Wait Time: 4.000 sec

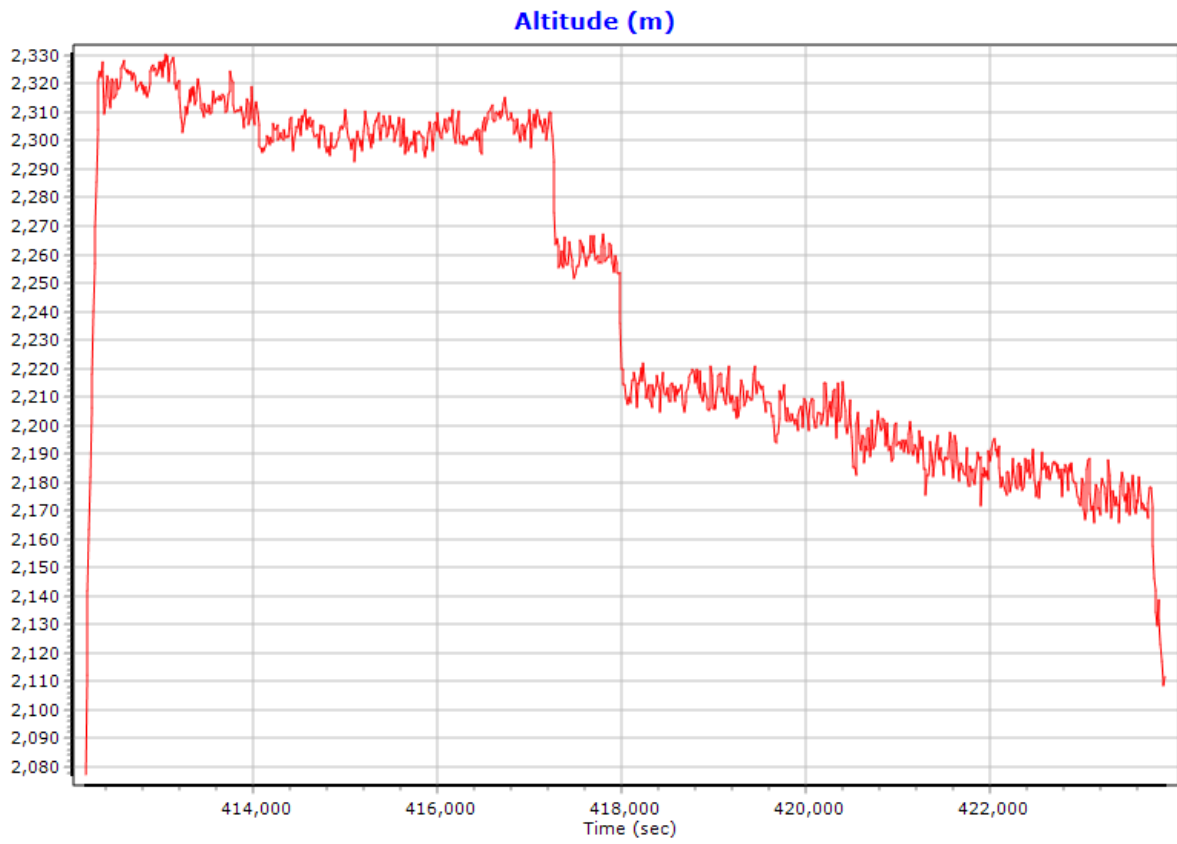
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	392789.000	405696.000	12907.000	End of file

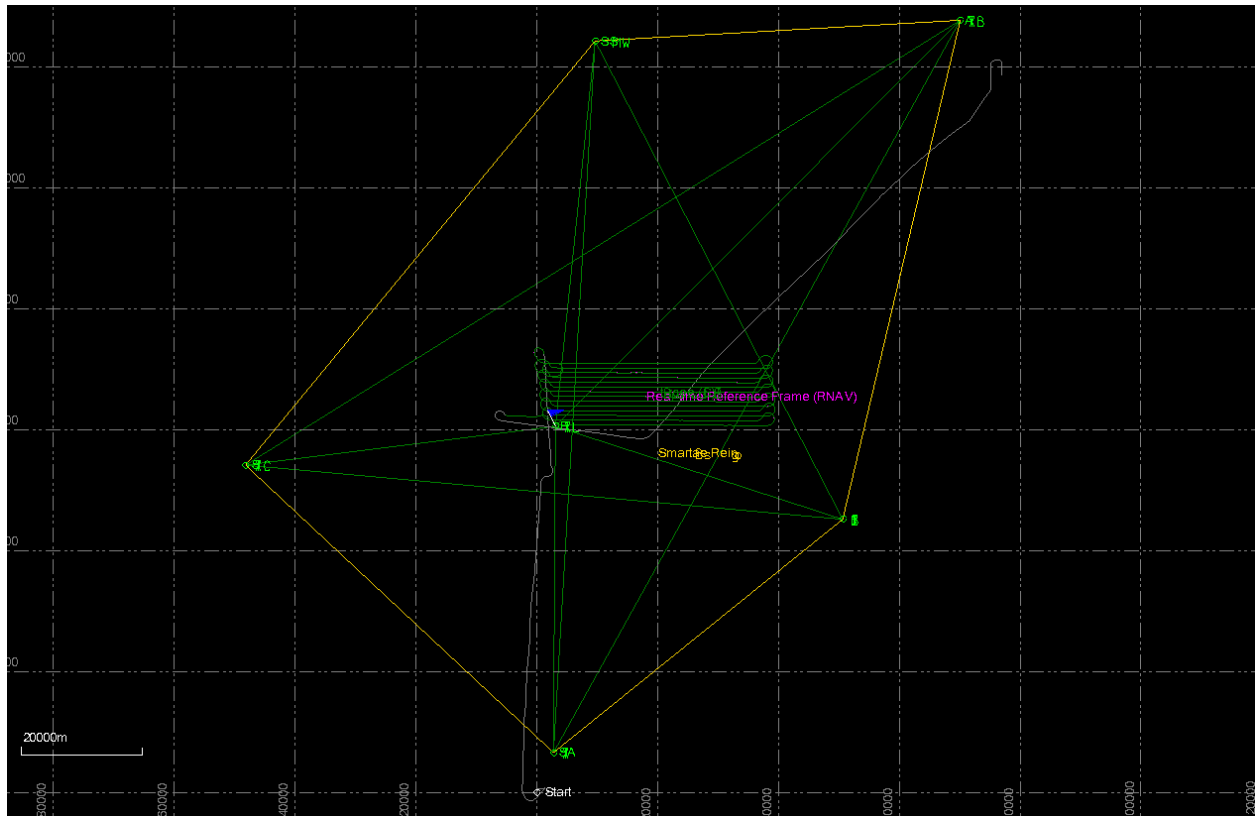
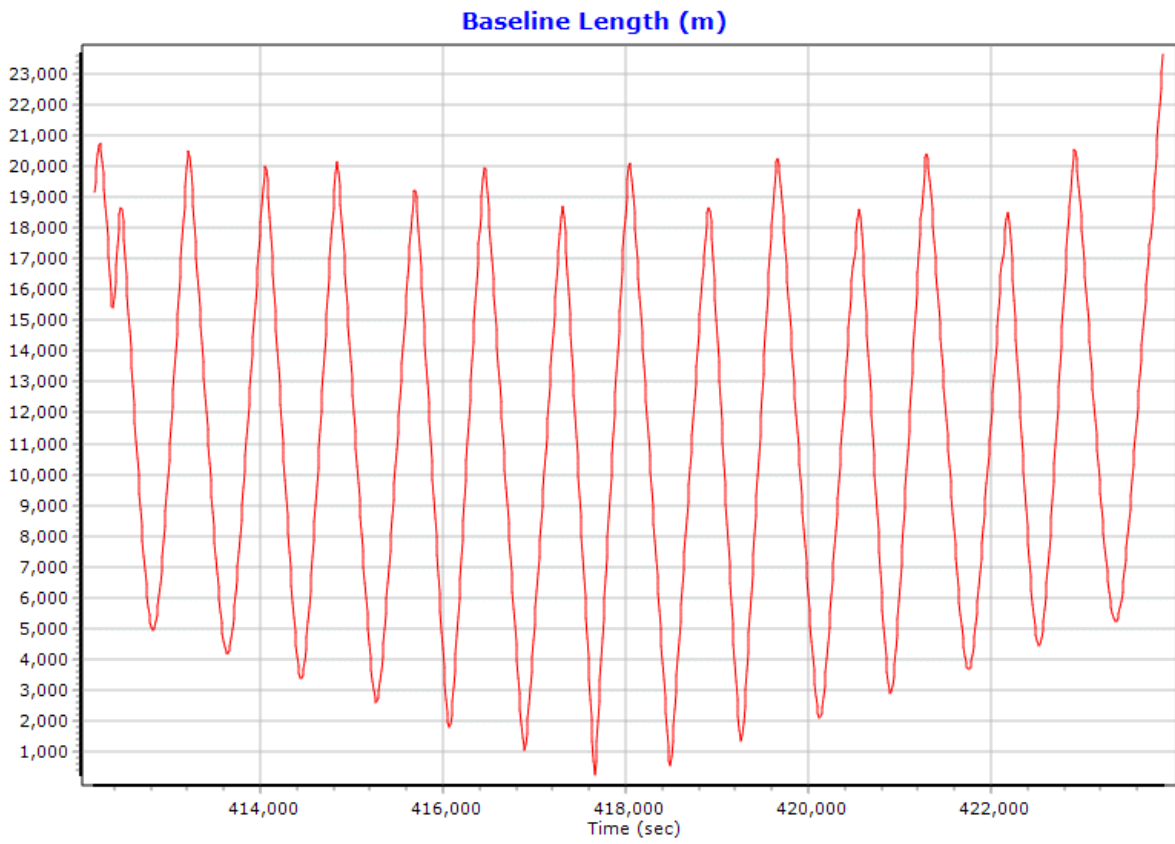
OK Cancel

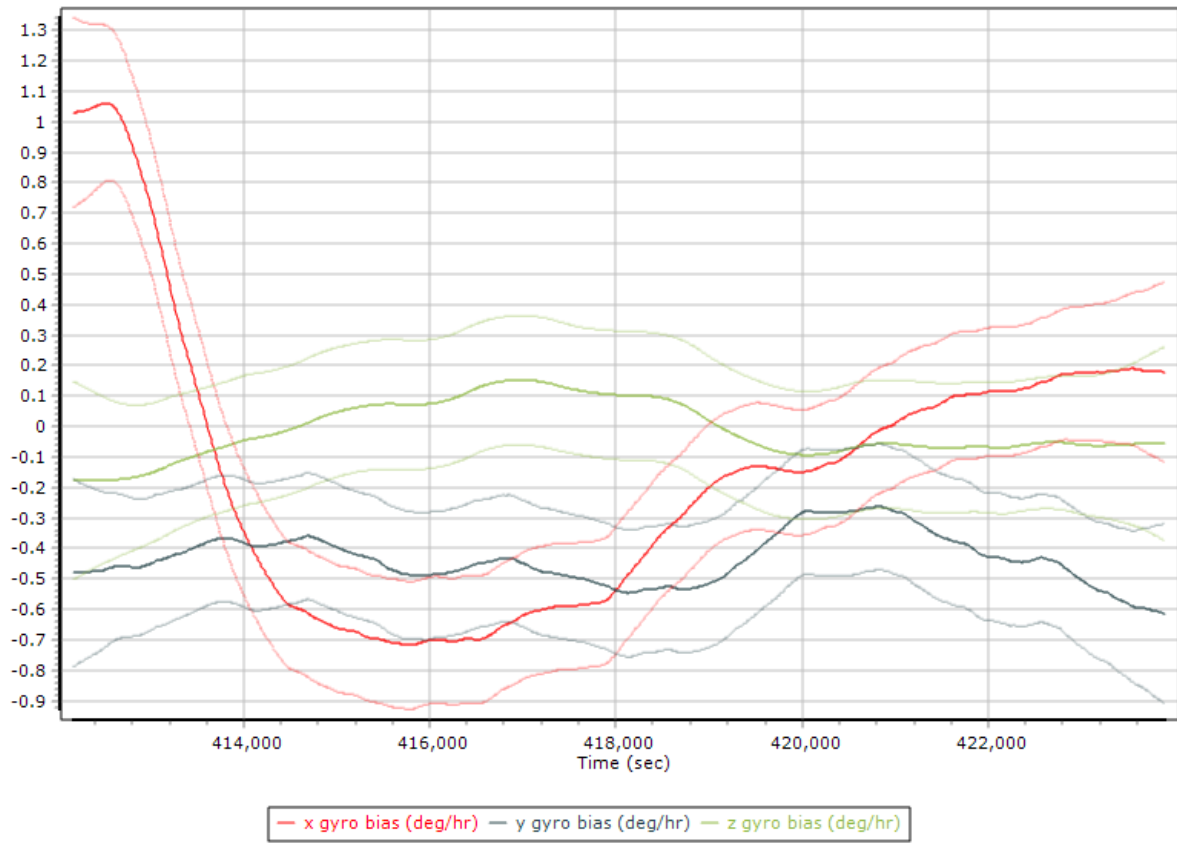
CAU18o81B

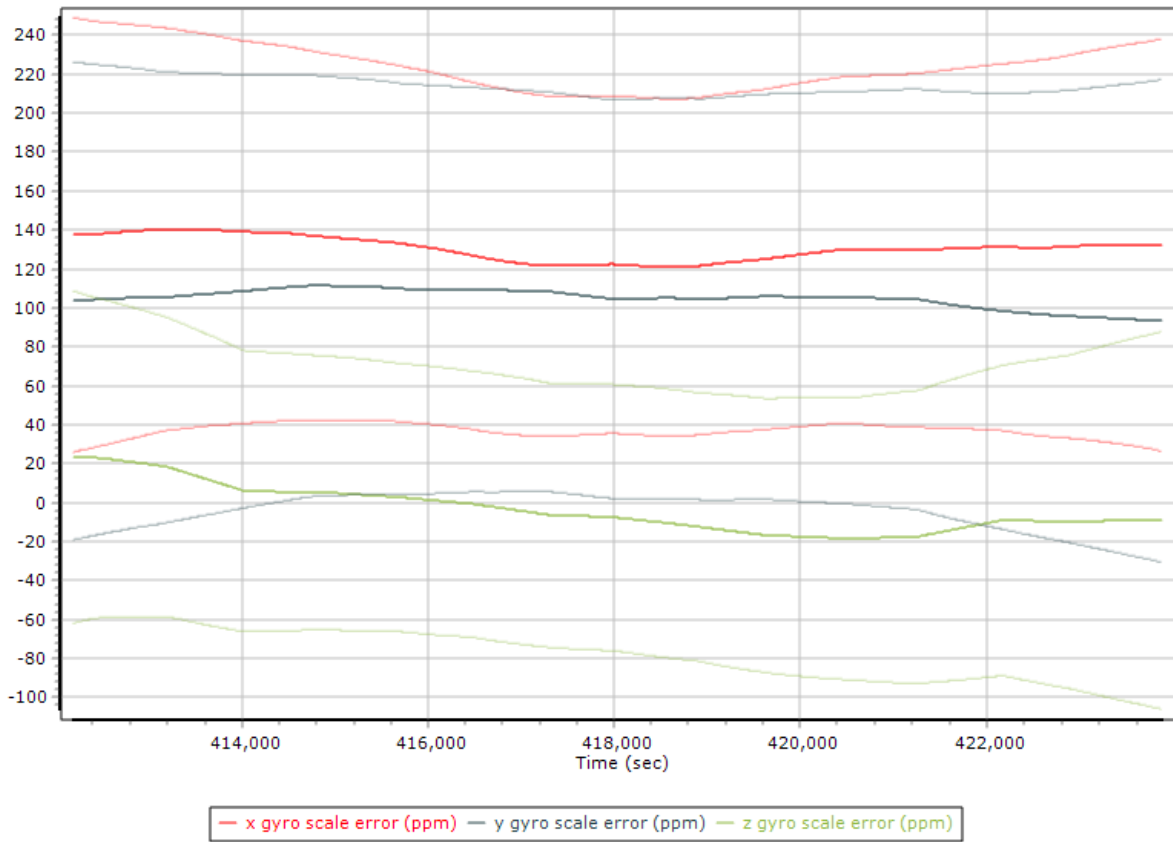












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

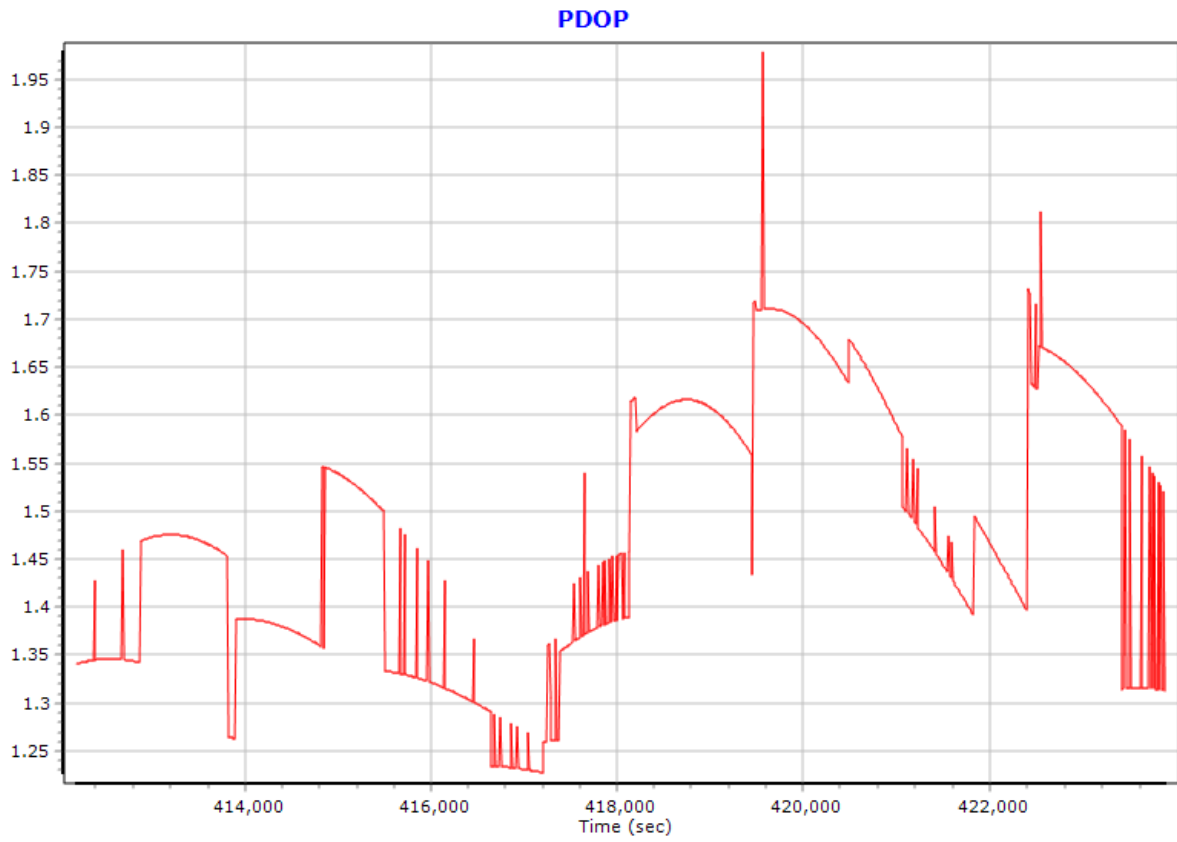
Aircraft to Reference Mounting Angles

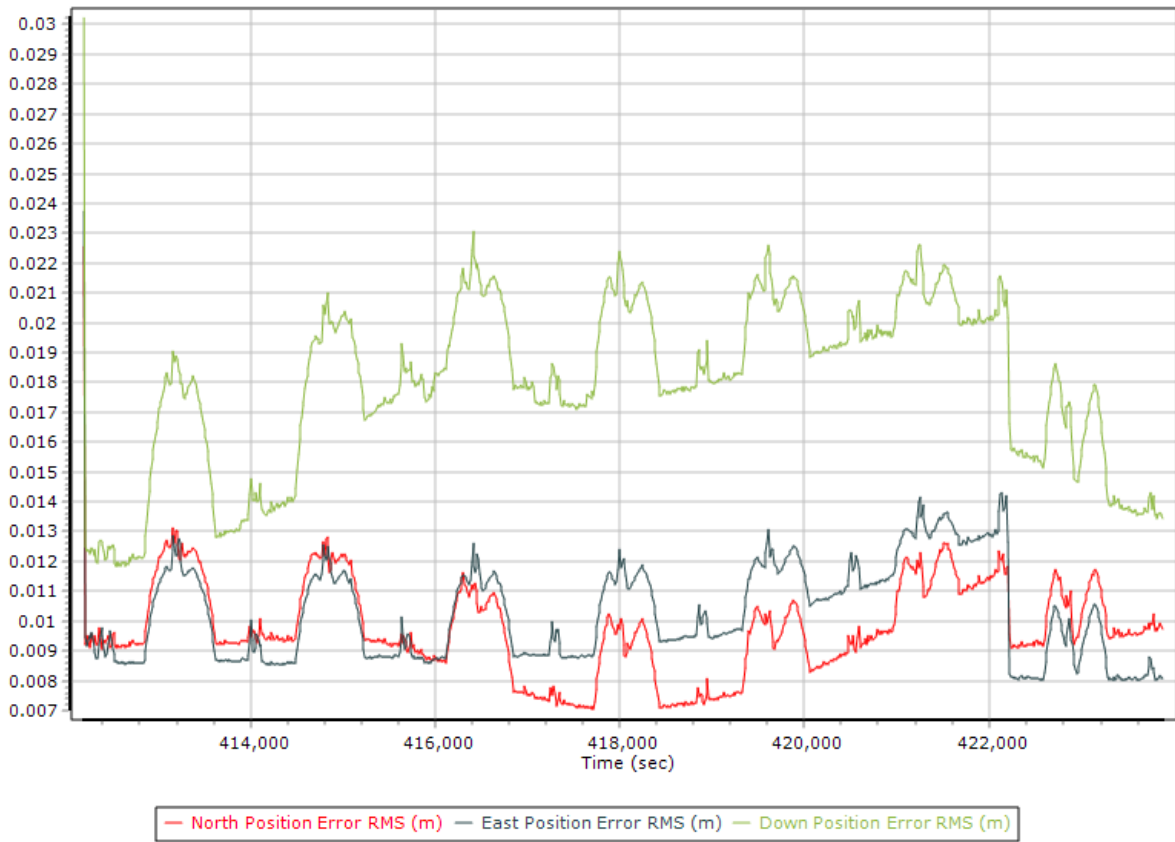
X:

Y:

Z:

OK Cancel





Project Settings [X]

- General Information
- Units
- View
- Rover Import
- Satellite Selection**
- GNSS-Inertial Processor
- Export
- Camera
- LIDAR
- SAR

Disable Satellites

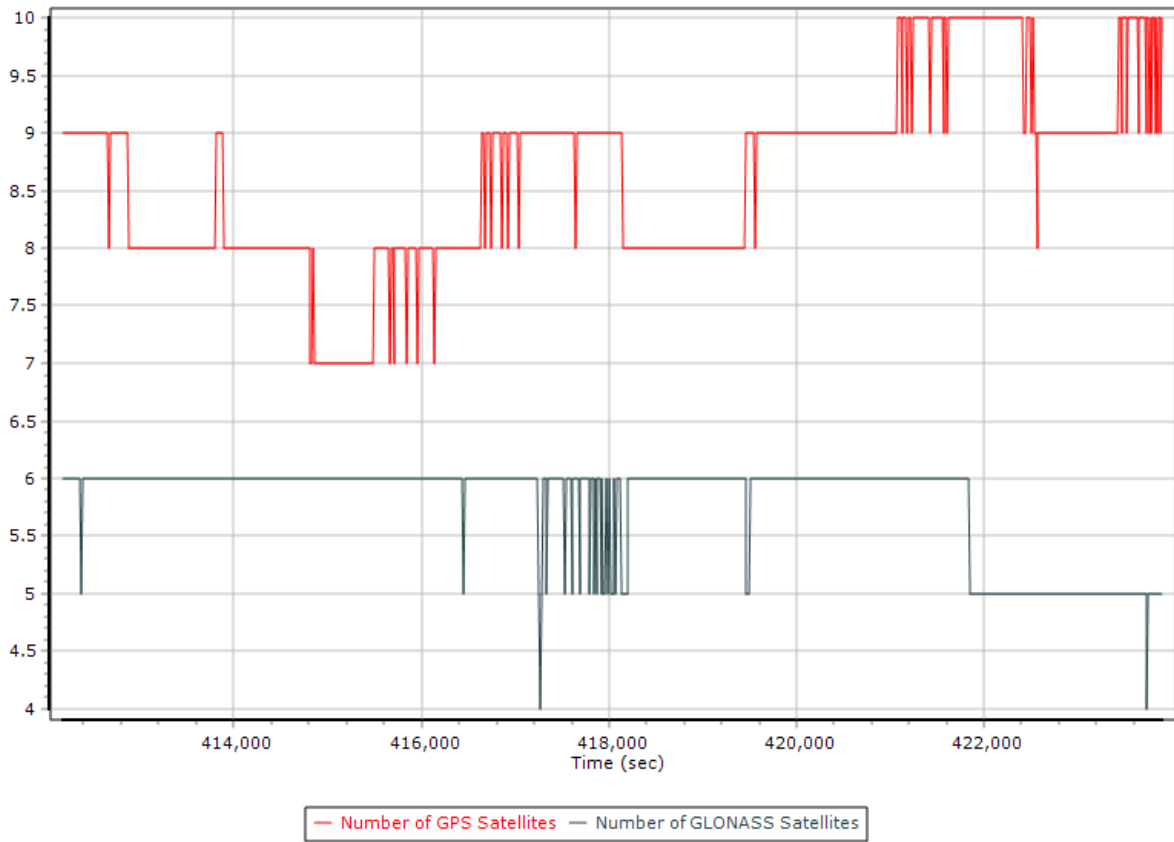
GPS | GLONASS | BEIDOU | QZSS

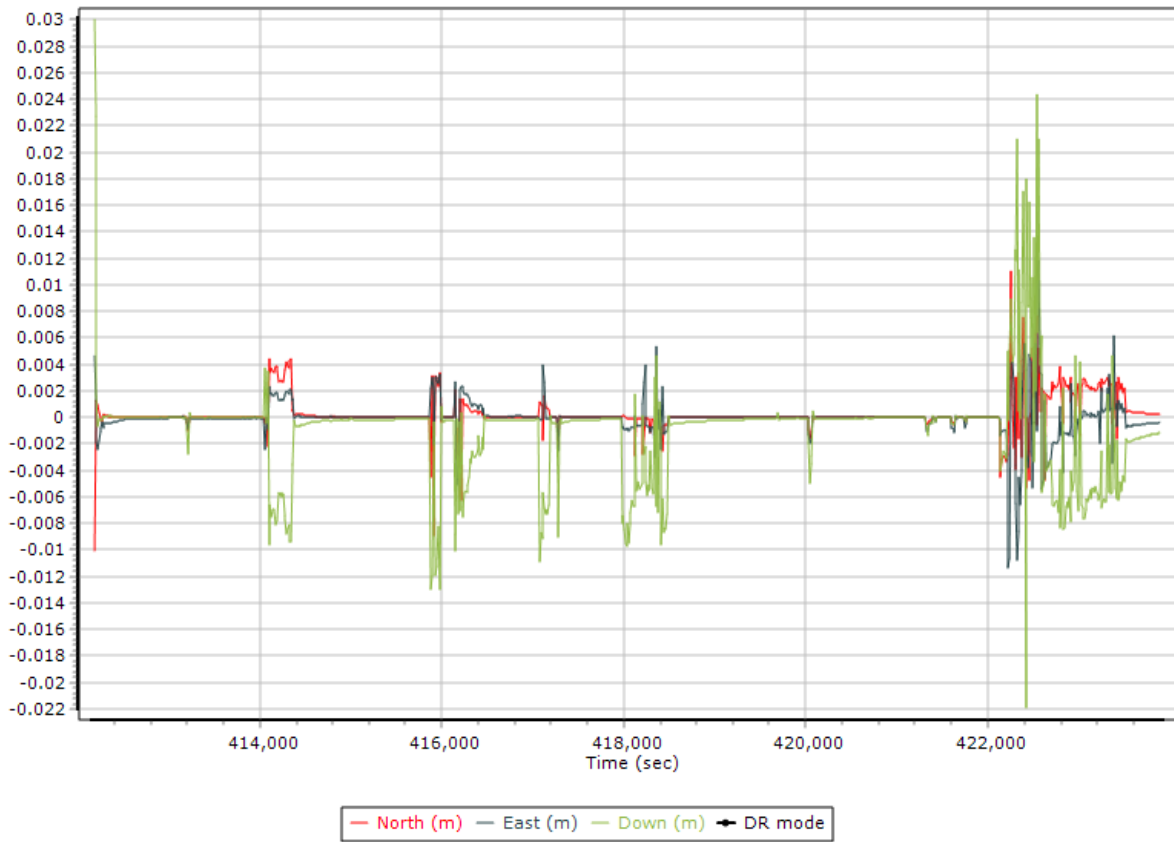
<input type="checkbox"/> PRN 1	<input type="checkbox"/> PRN 10	<input type="checkbox"/> PRN 19	<input type="checkbox"/> PRN 28
<input type="checkbox"/> PRN 2	<input type="checkbox"/> PRN 11	<input type="checkbox"/> PRN 20	<input type="checkbox"/> PRN 29
<input type="checkbox"/> PRN 3	<input type="checkbox"/> PRN 12	<input type="checkbox"/> PRN 21	<input type="checkbox"/> PRN 30
<input type="checkbox"/> PRN 4	<input type="checkbox"/> PRN 13	<input type="checkbox"/> PRN 22	<input type="checkbox"/> PRN 31
<input type="checkbox"/> PRN 5	<input type="checkbox"/> PRN 14	<input type="checkbox"/> PRN 23	<input type="checkbox"/> PRN 32
<input type="checkbox"/> PRN 6	<input type="checkbox"/> PRN 15	<input type="checkbox"/> PRN 24	
<input type="checkbox"/> PRN 7	<input type="checkbox"/> PRN 16	<input type="checkbox"/> PRN 25	
<input type="checkbox"/> PRN 8	<input type="checkbox"/> PRN 17	<input type="checkbox"/> PRN 26	
<input type="checkbox"/> PRN 9	<input type="checkbox"/> PRN 18	<input type="checkbox"/> PRN 27	

Elevation Mask Angle:

Force GPS Only

OK Cancel





Project Settings [X]

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

Timing

Start: 409770.430
 End: 426021.000
 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

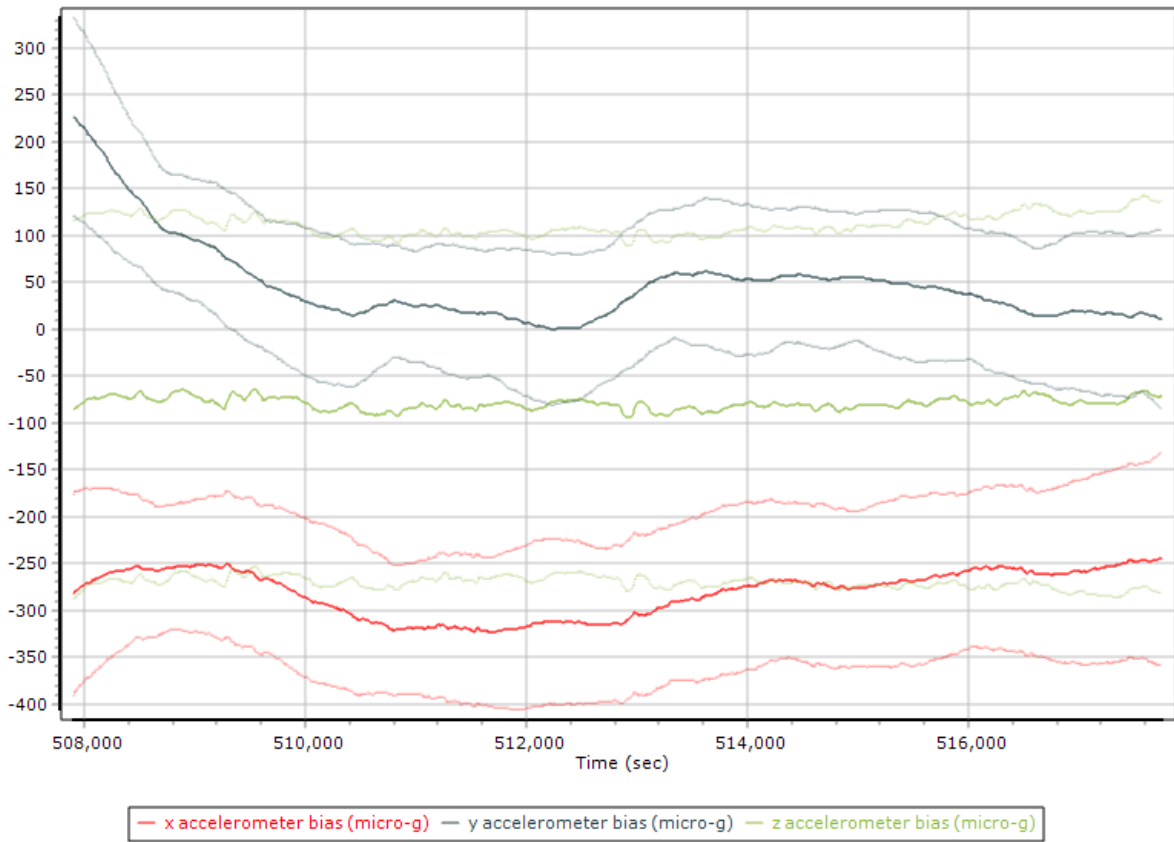
Processable Time Windows

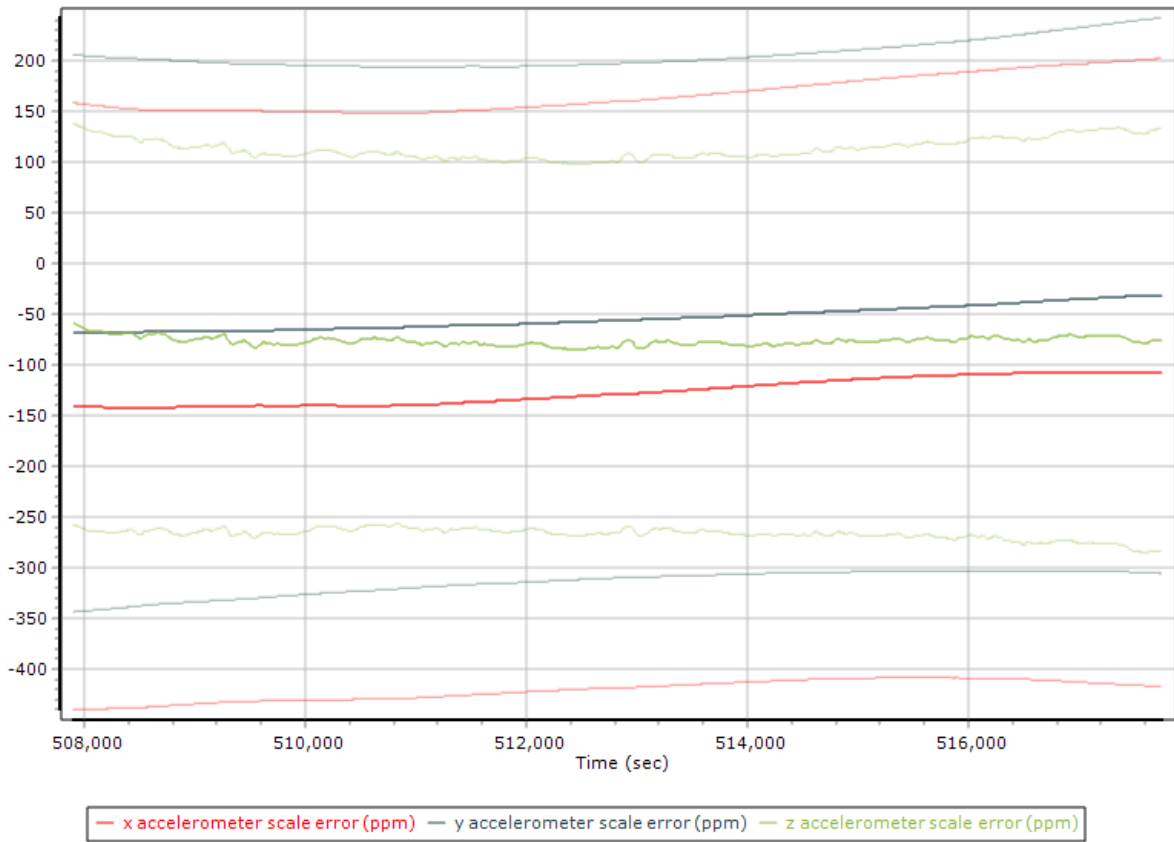
Start after launch Wait Time: 4.000 sec

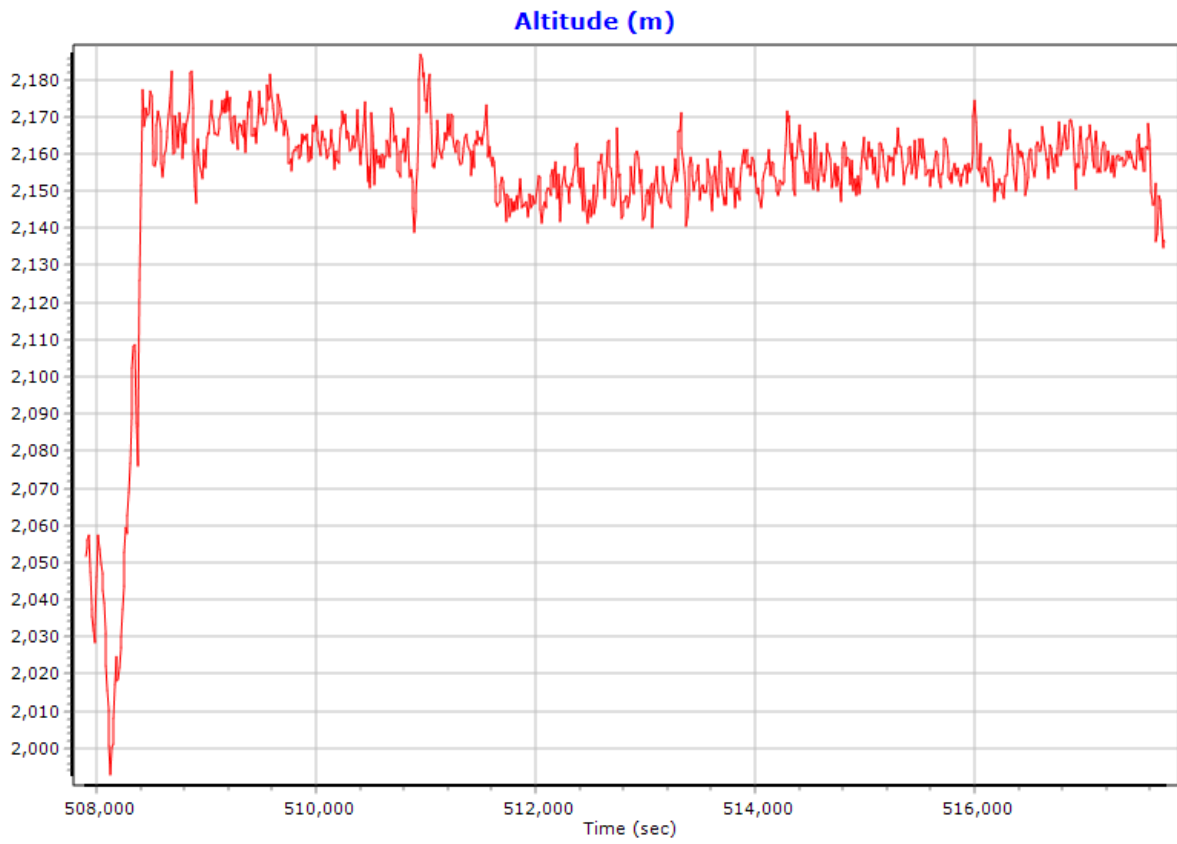
	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	409770.430	426021.000	16250.570	End of file

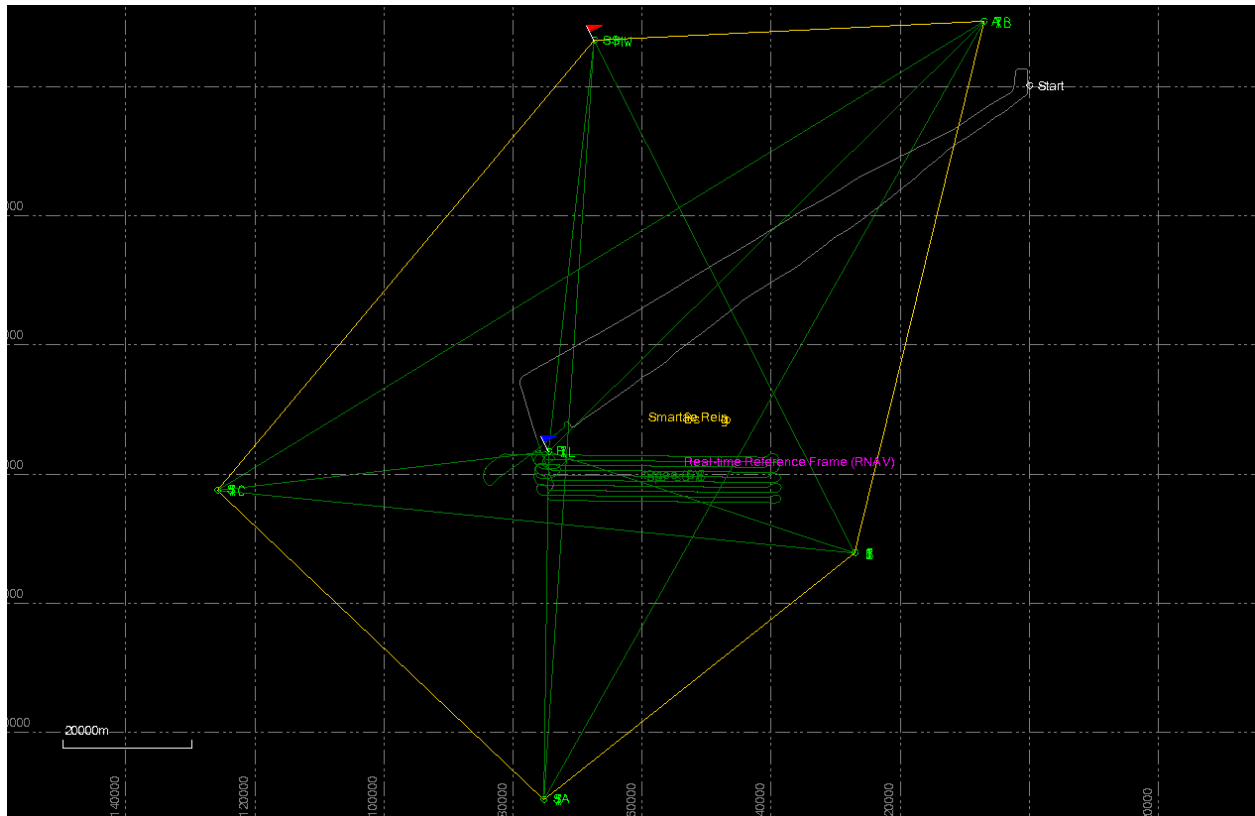
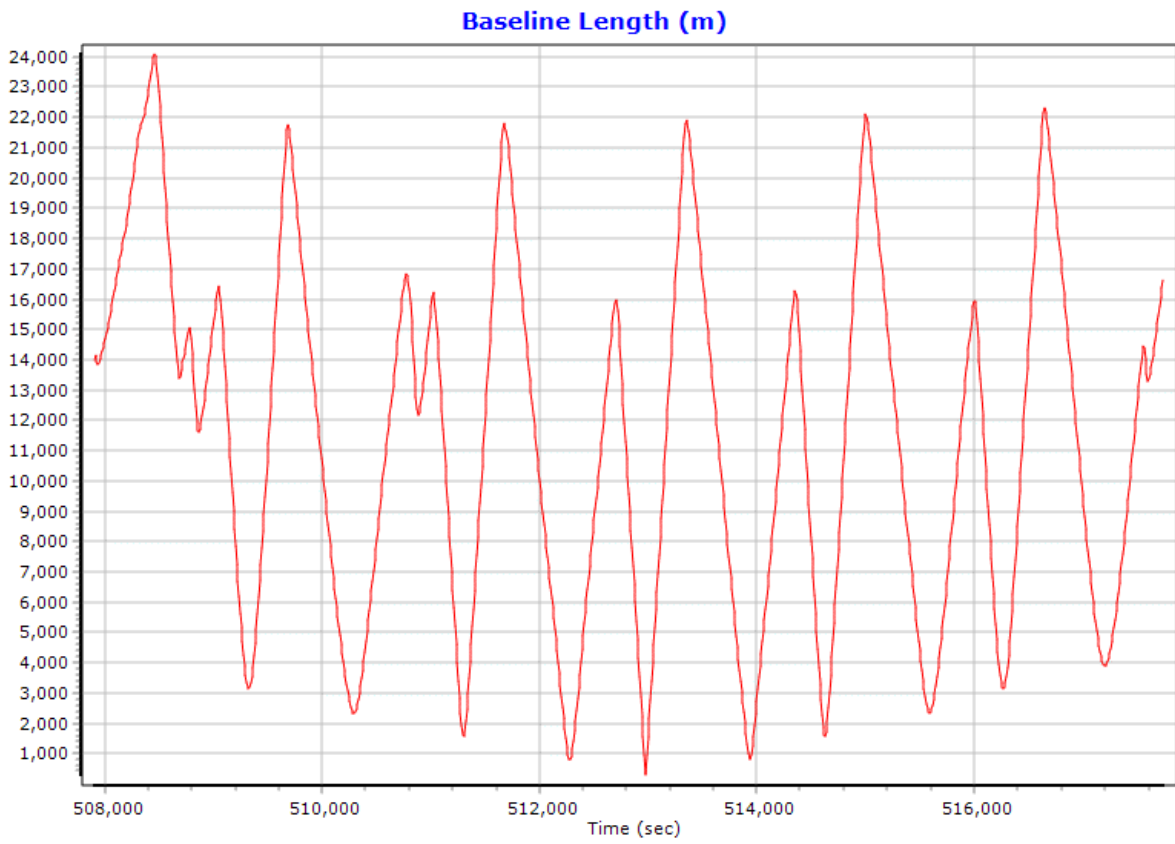
OK Cancel

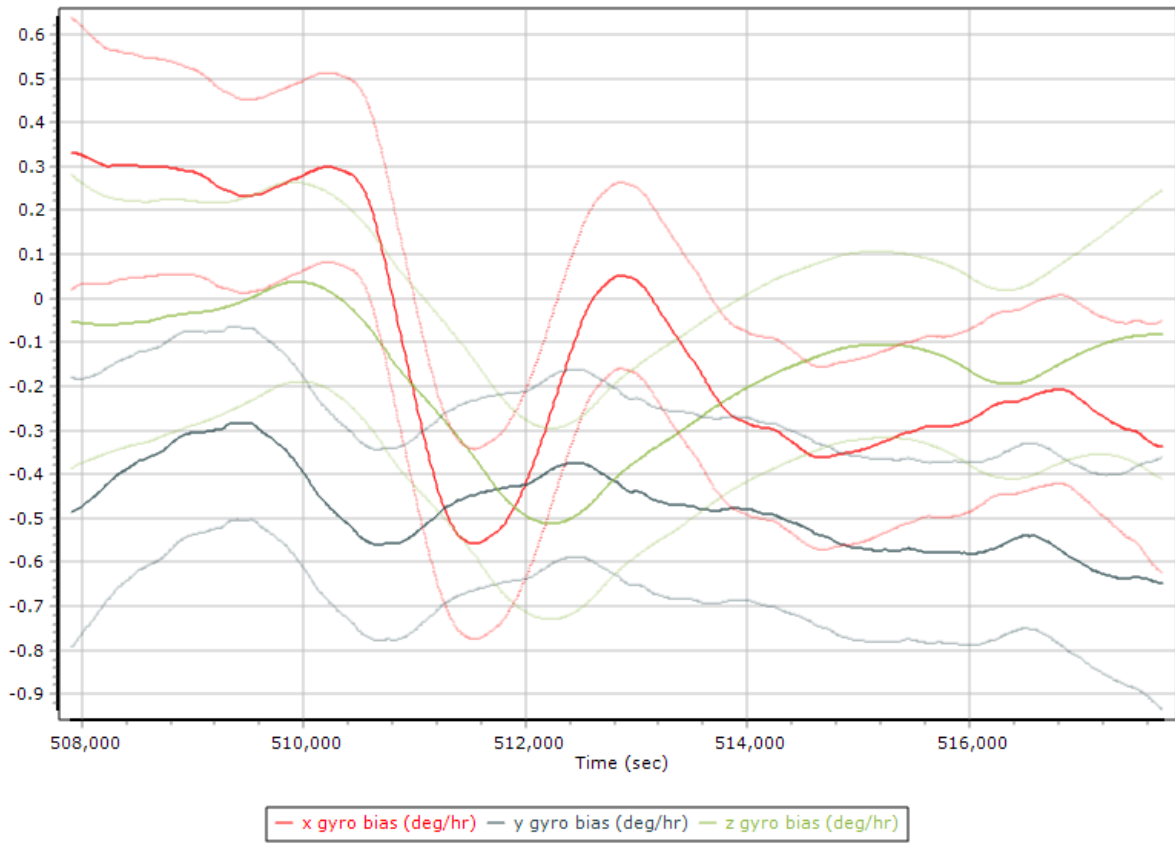
CAU18082A

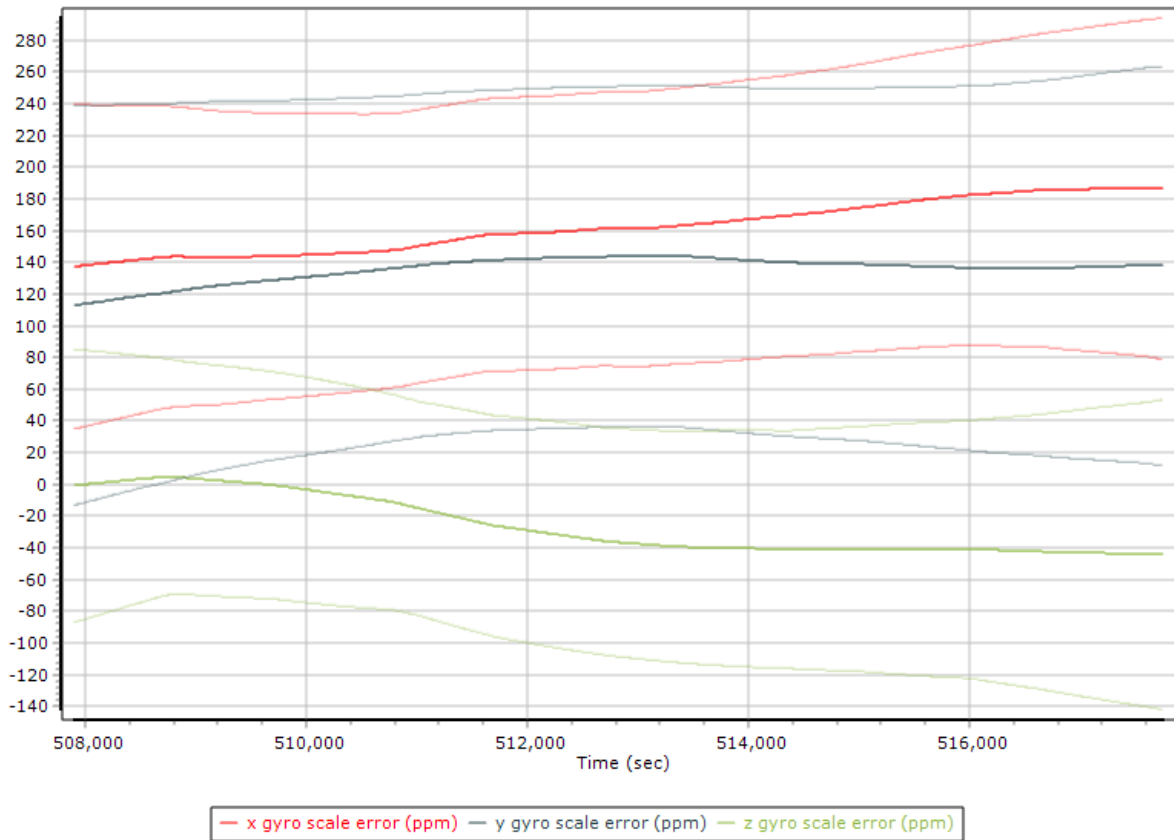












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

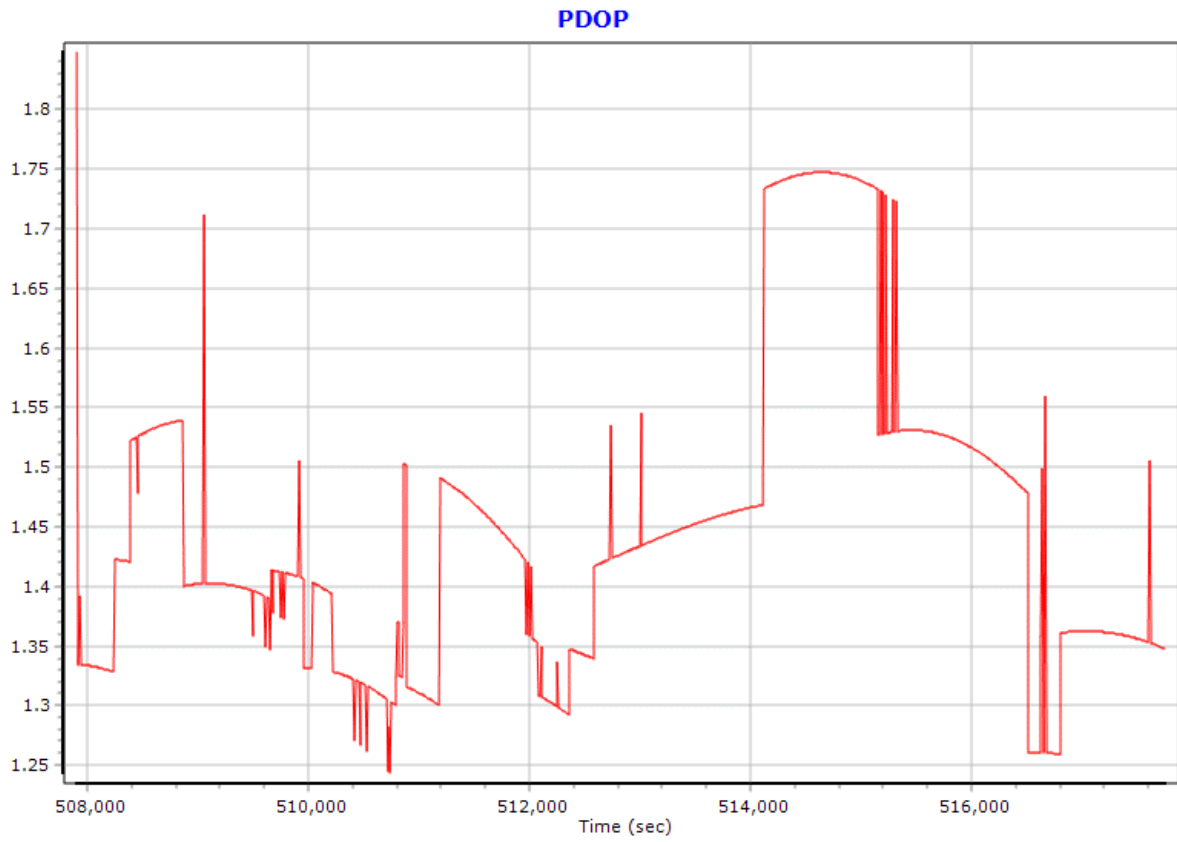
Aircraft to Reference Mounting Angles

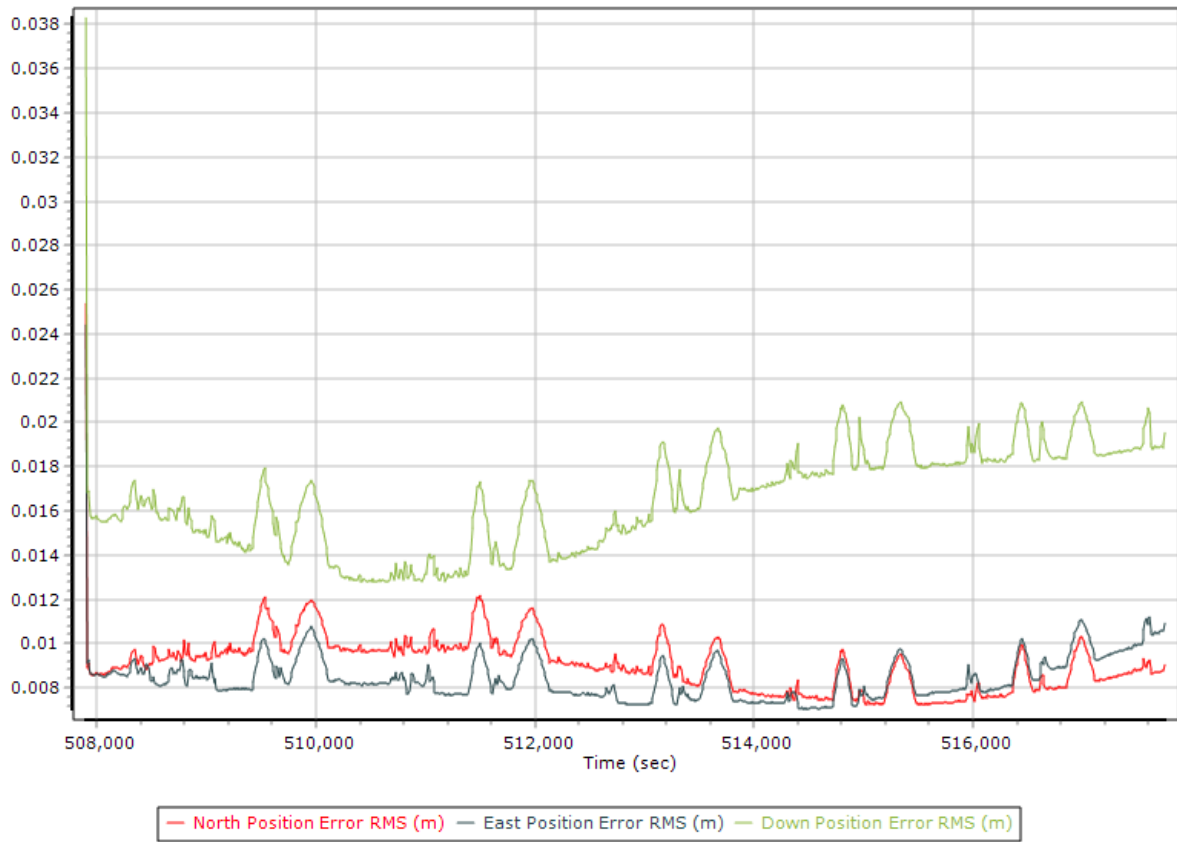
X:

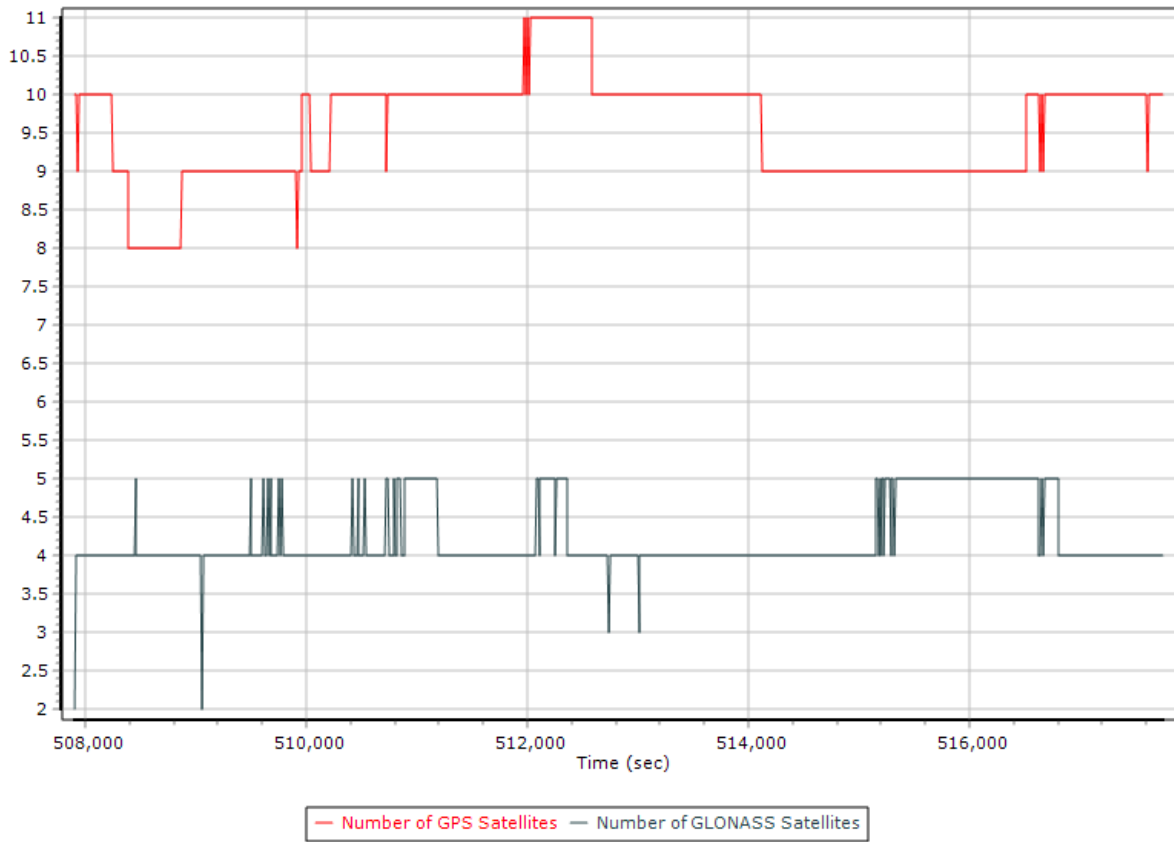
Y:

Z:

OK Cancel







Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
- Export
- Camera
- LIDAR
- SAR

Disable Satellites

GPS | GLONASS | BEIDOU | QZSS

<input type="checkbox"/> PRN 1	<input type="checkbox"/> PRN 10	<input type="checkbox"/> PRN 19	<input type="checkbox"/> PRN 28
<input type="checkbox"/> PRN 2	<input type="checkbox"/> PRN 11	<input type="checkbox"/> PRN 20	<input type="checkbox"/> PRN 29
<input type="checkbox"/> PRN 3	<input type="checkbox"/> PRN 12	<input type="checkbox"/> PRN 21	<input type="checkbox"/> PRN 30
<input type="checkbox"/> PRN 4	<input type="checkbox"/> PRN 13	<input type="checkbox"/> PRN 22	<input type="checkbox"/> PRN 31
<input type="checkbox"/> PRN 5	<input type="checkbox"/> PRN 14	<input type="checkbox"/> PRN 23	<input type="checkbox"/> PRN 32
<input type="checkbox"/> PRN 6	<input type="checkbox"/> PRN 15	<input type="checkbox"/> PRN 24	
<input type="checkbox"/> PRN 7	<input type="checkbox"/> PRN 16	<input type="checkbox"/> PRN 25	
<input type="checkbox"/> PRN 8	<input type="checkbox"/> PRN 17	<input type="checkbox"/> PRN 26	
<input type="checkbox"/> PRN 9	<input type="checkbox"/> PRN 18	<input type="checkbox"/> PRN 27	

Elevation Mask Angle: 12.000 deg

Force GPS Only

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:

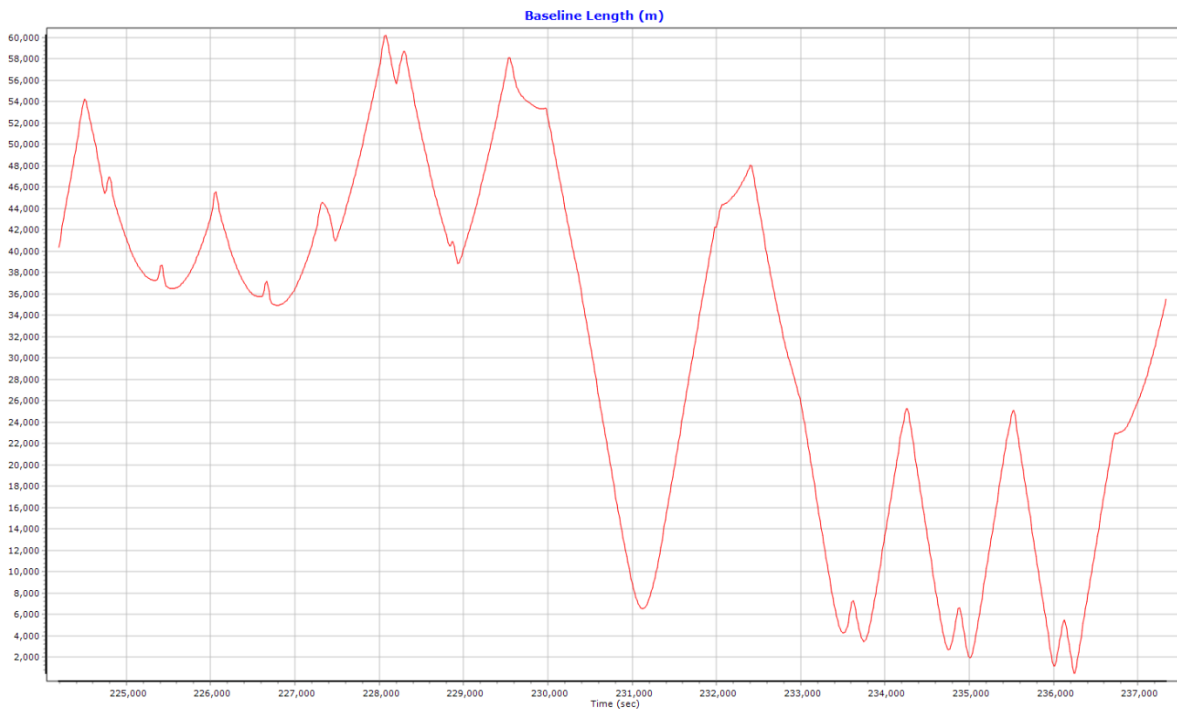
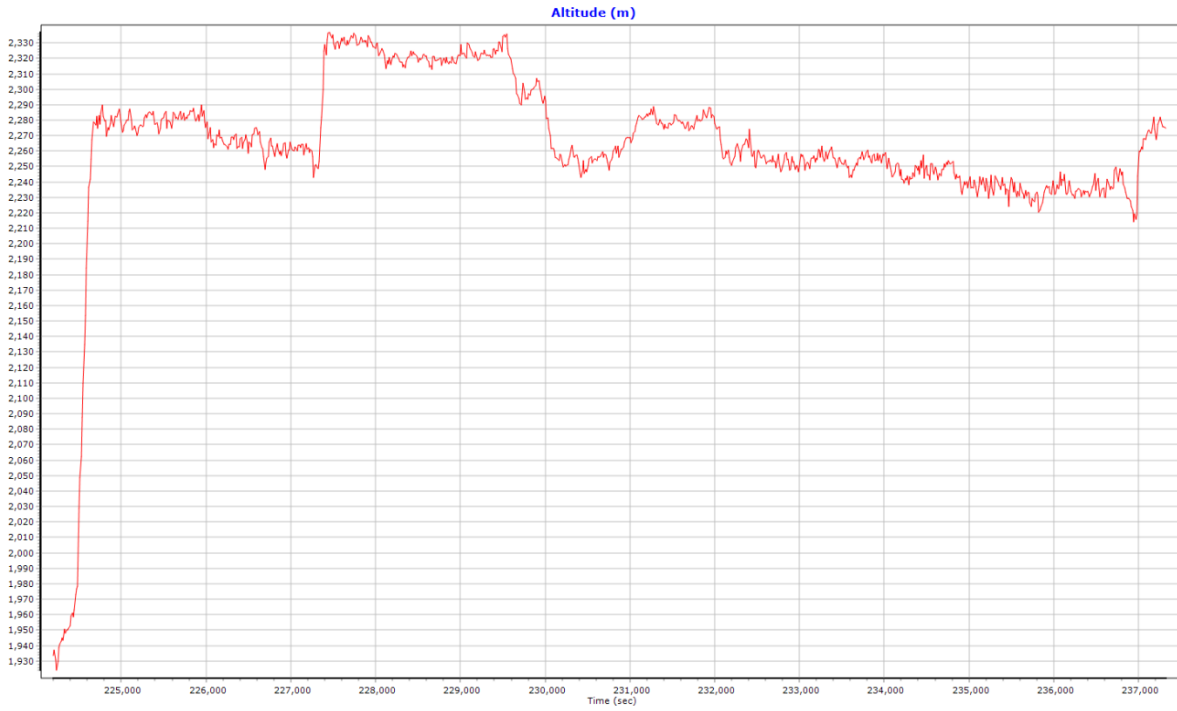
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

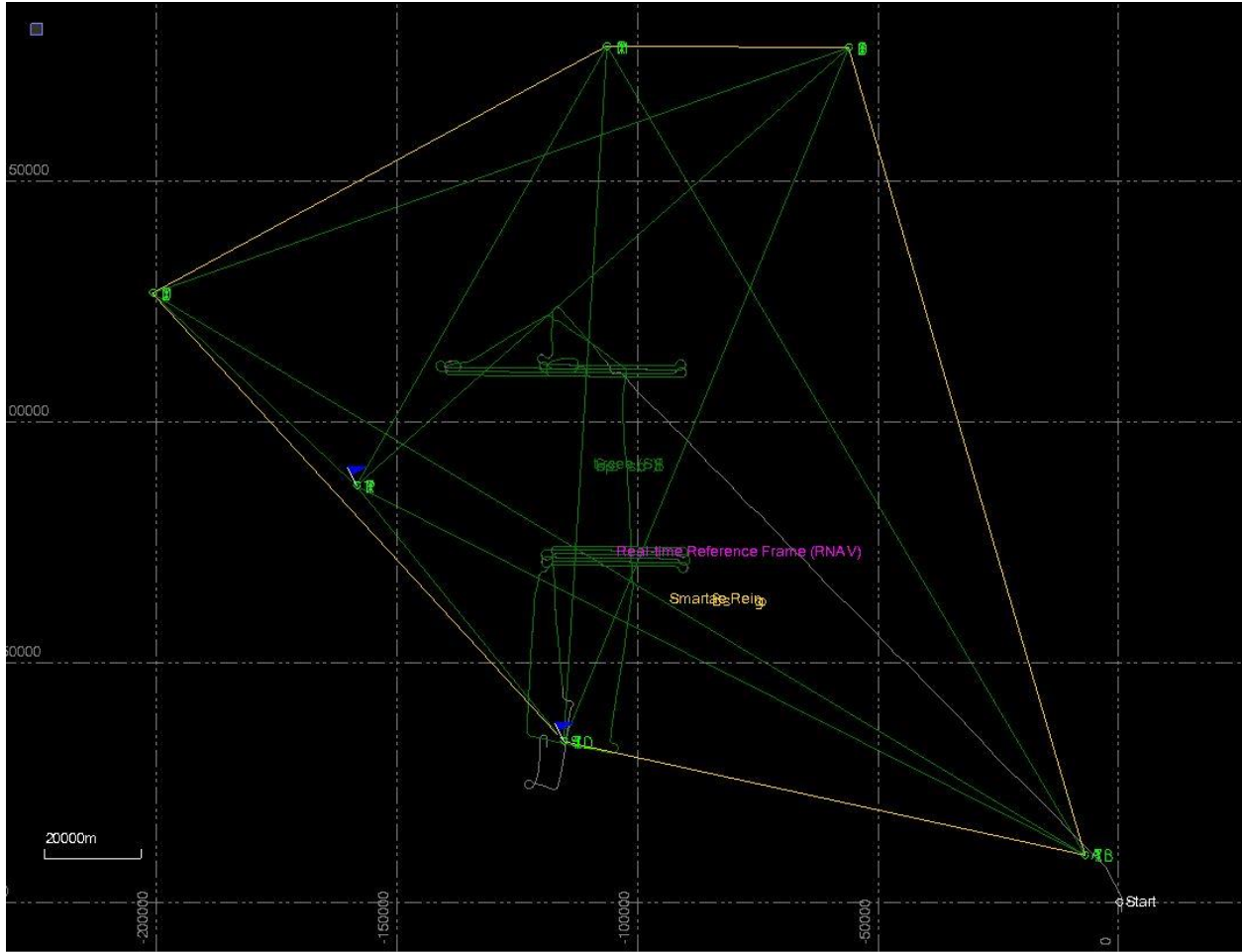
Processable Time Windows

Start after launch Wait Time: sec

	Start Time	End Time	Duration	Reason For End
<input checked="" type="checkbox"/>	504376.000	519503.000	15127.000	End of file

CAU18100A





Project Settings

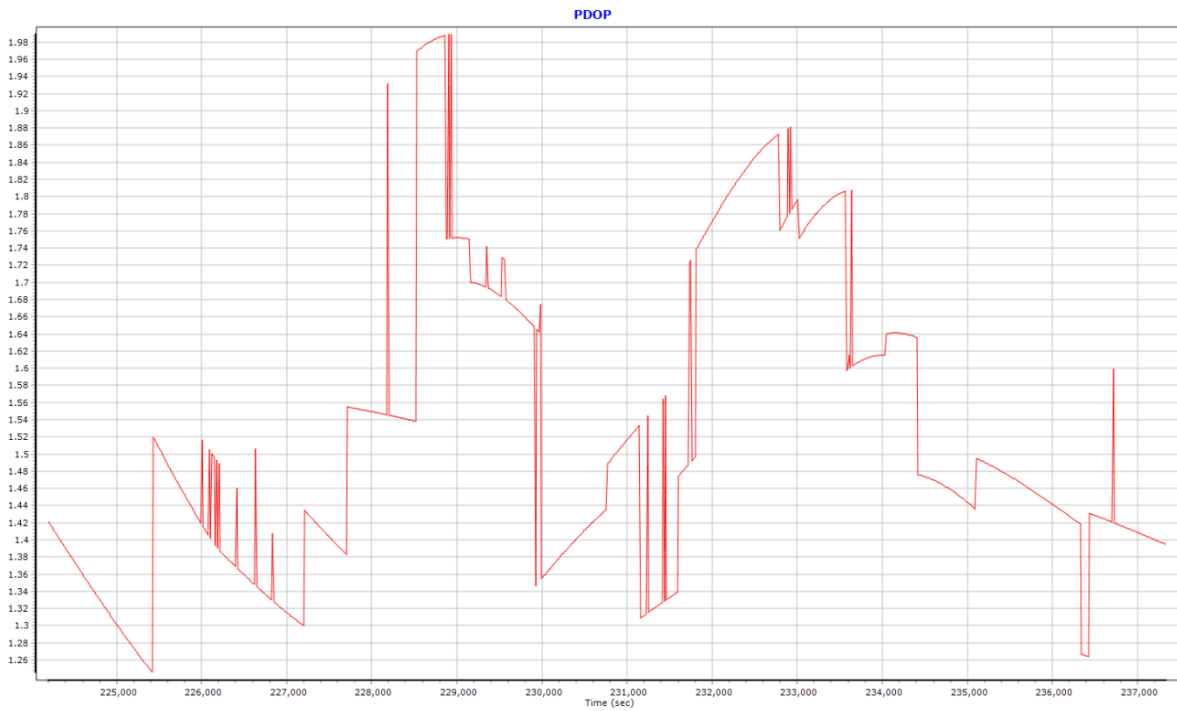
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

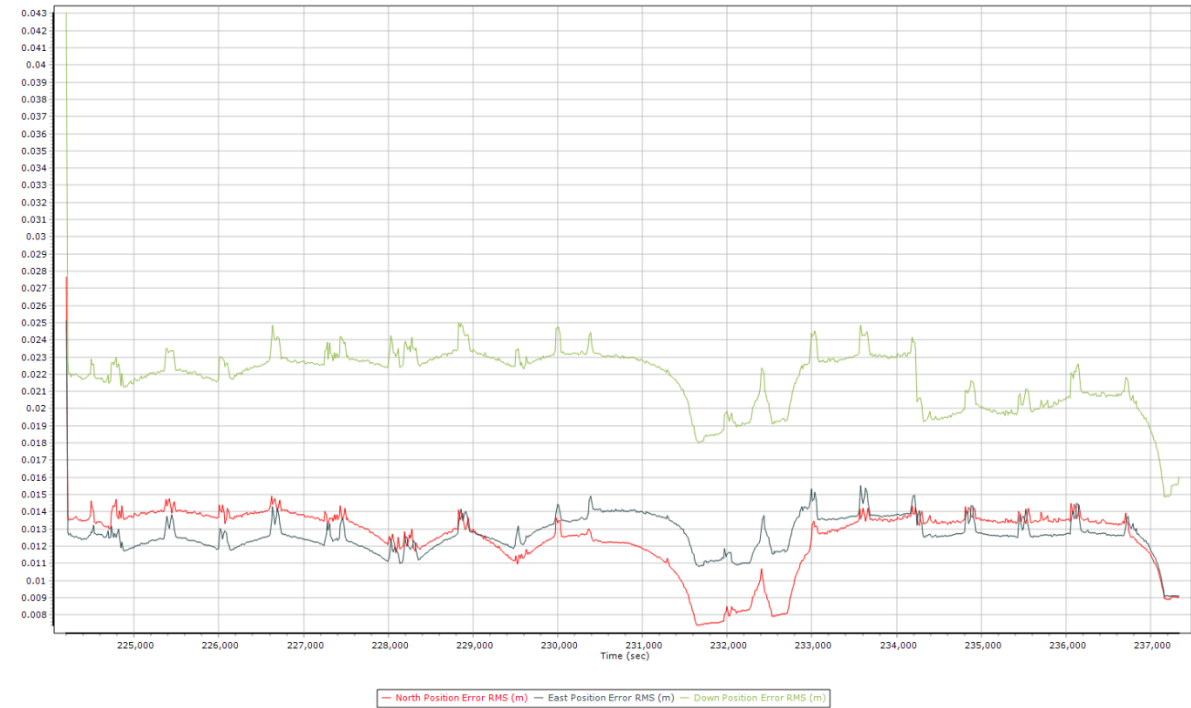
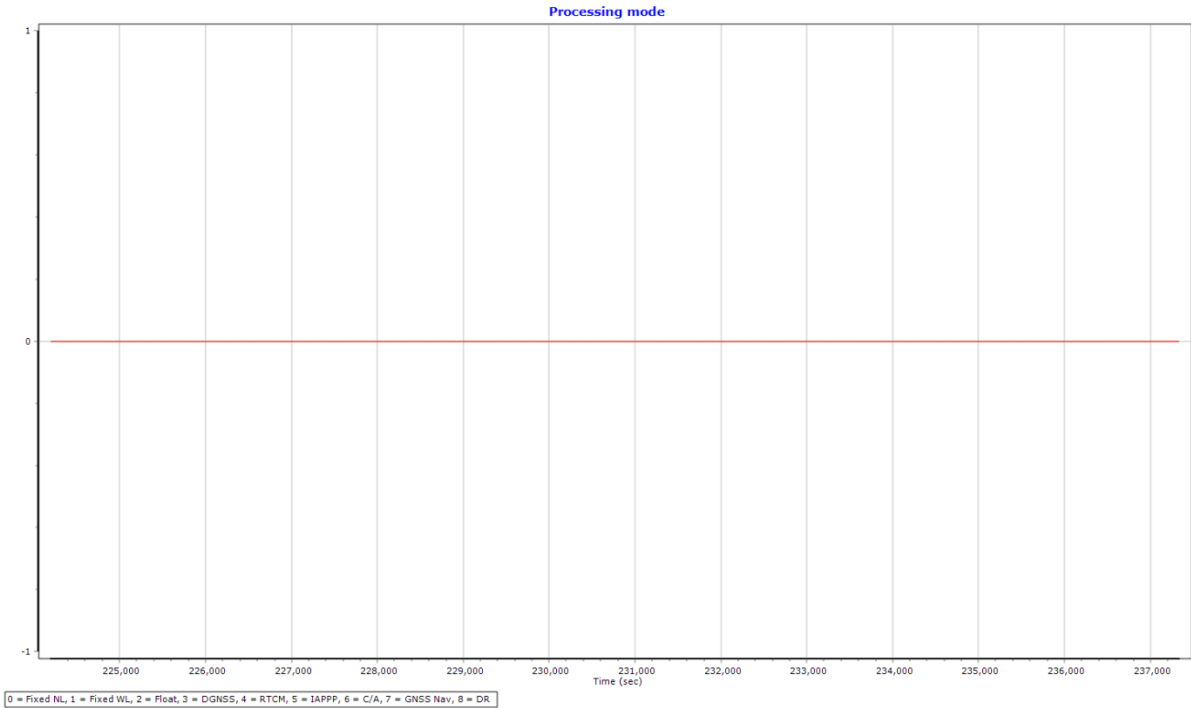
Reference to IMU Lever Arm		Reference to IMU Mounting Angles	
X	0.034 m	X	0.000 deg
Y	0.018 m	Y	0.000 deg
Z	-0.210 m	Z	180.000 deg

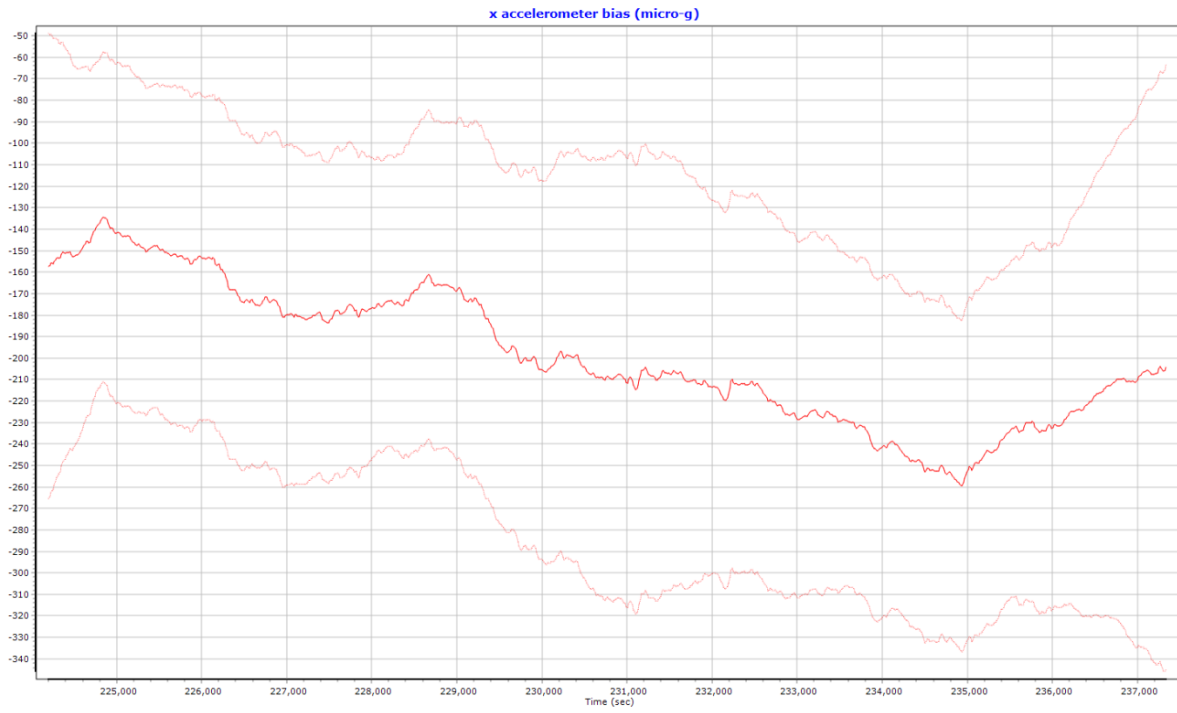
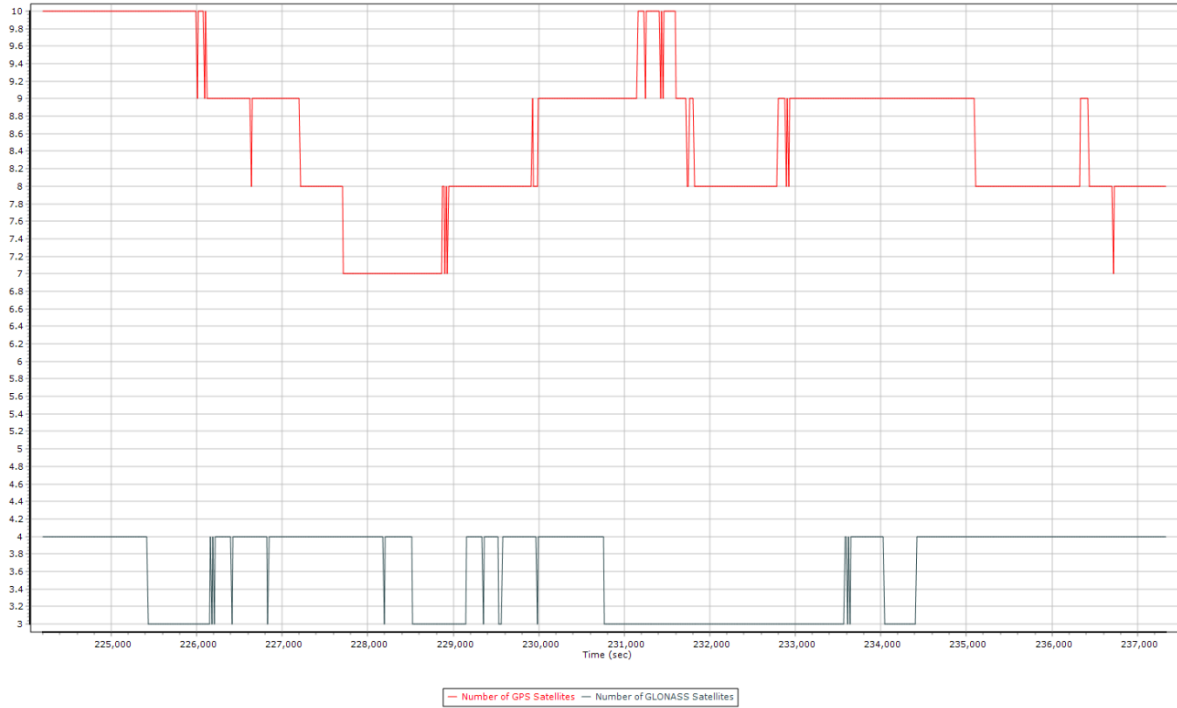
Reference to Primary GNSS Lever Arm		Aircraft to Reference Mounting Angles	
X	-0.174 m	X	0.000 deg
Y	-0.025 m	Y	0.000 deg
Z	-0.968 m	Z	0.000 deg

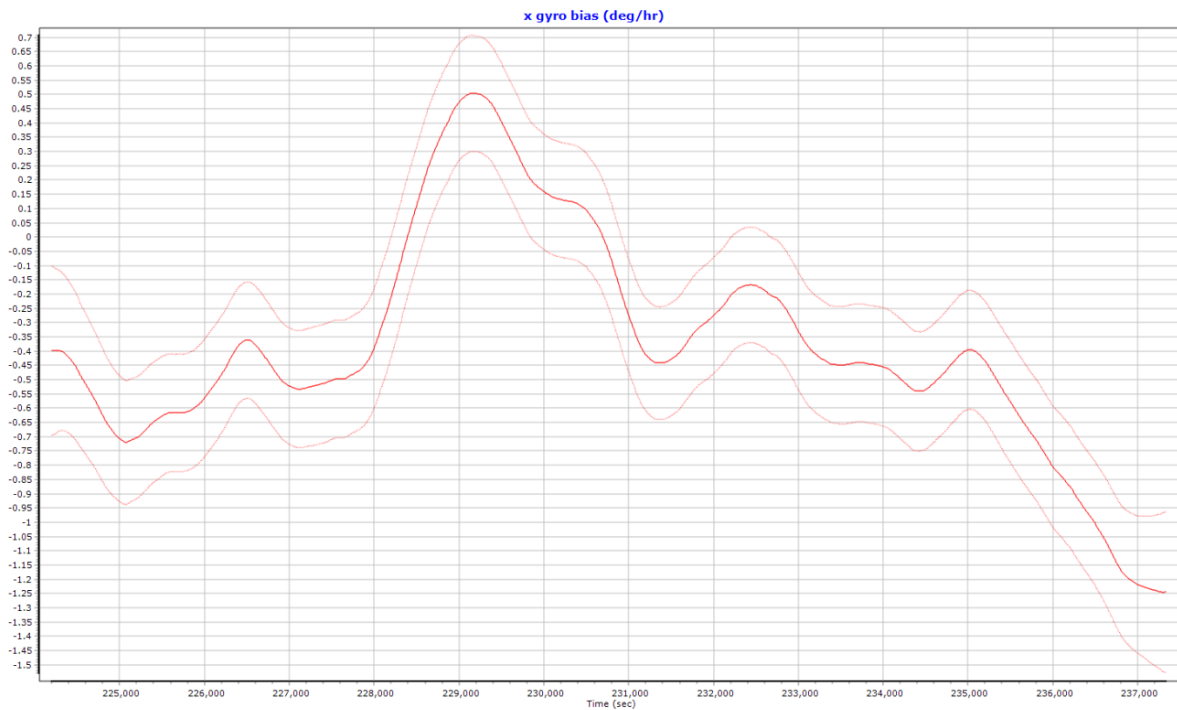
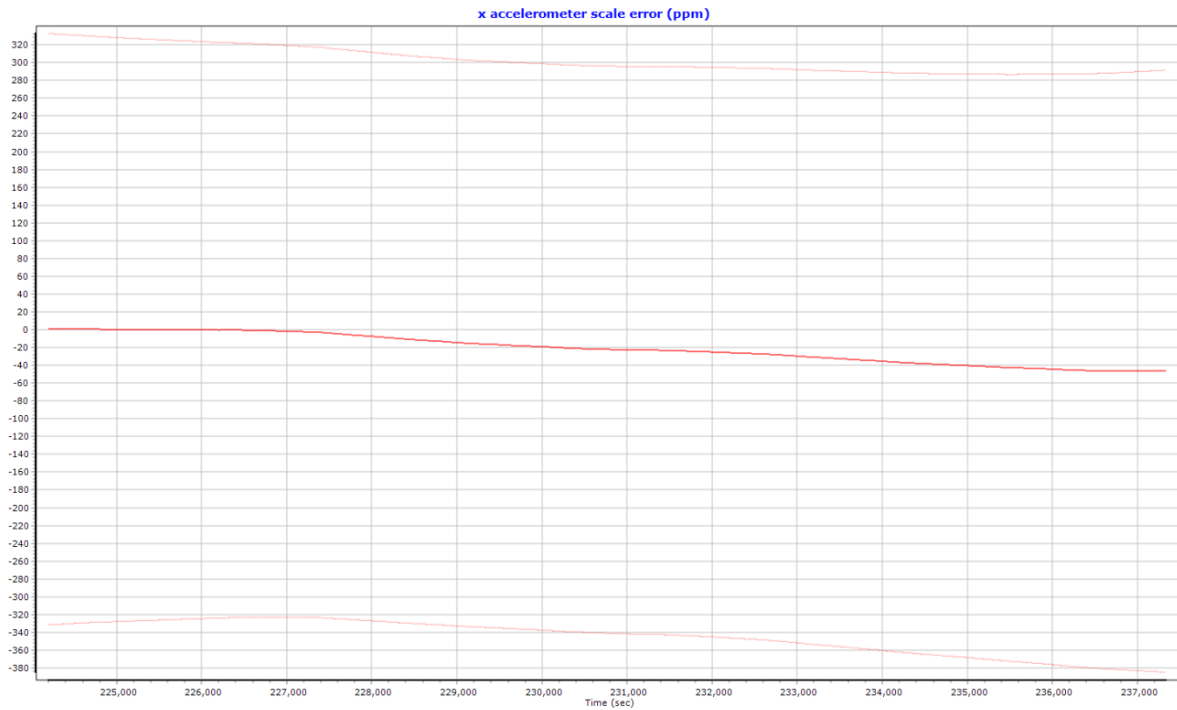
Standard Deviation: <3cm 10cm 50cm 1m 10m

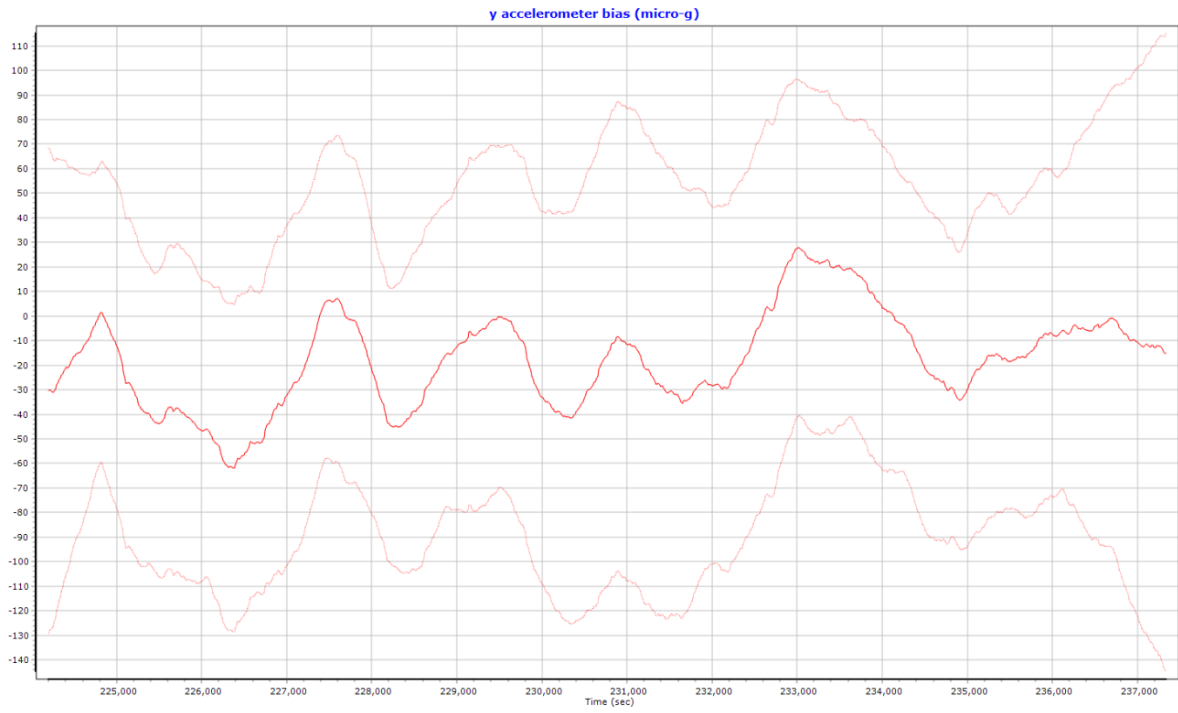
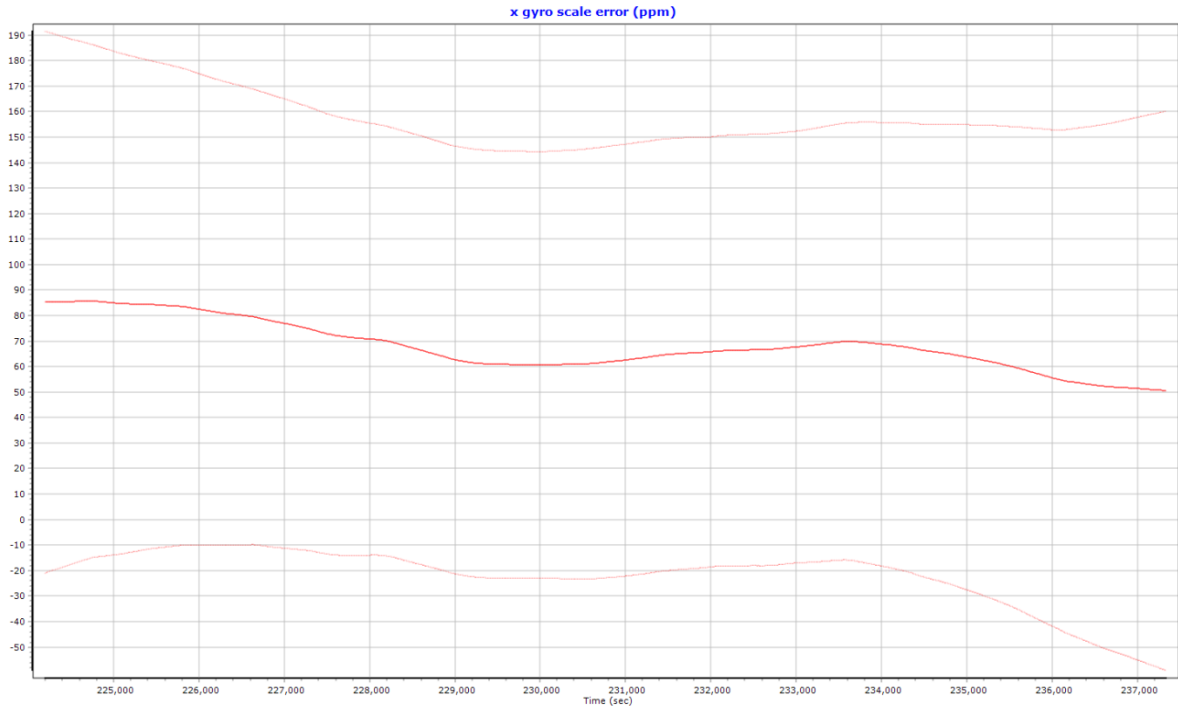
OK Cancel

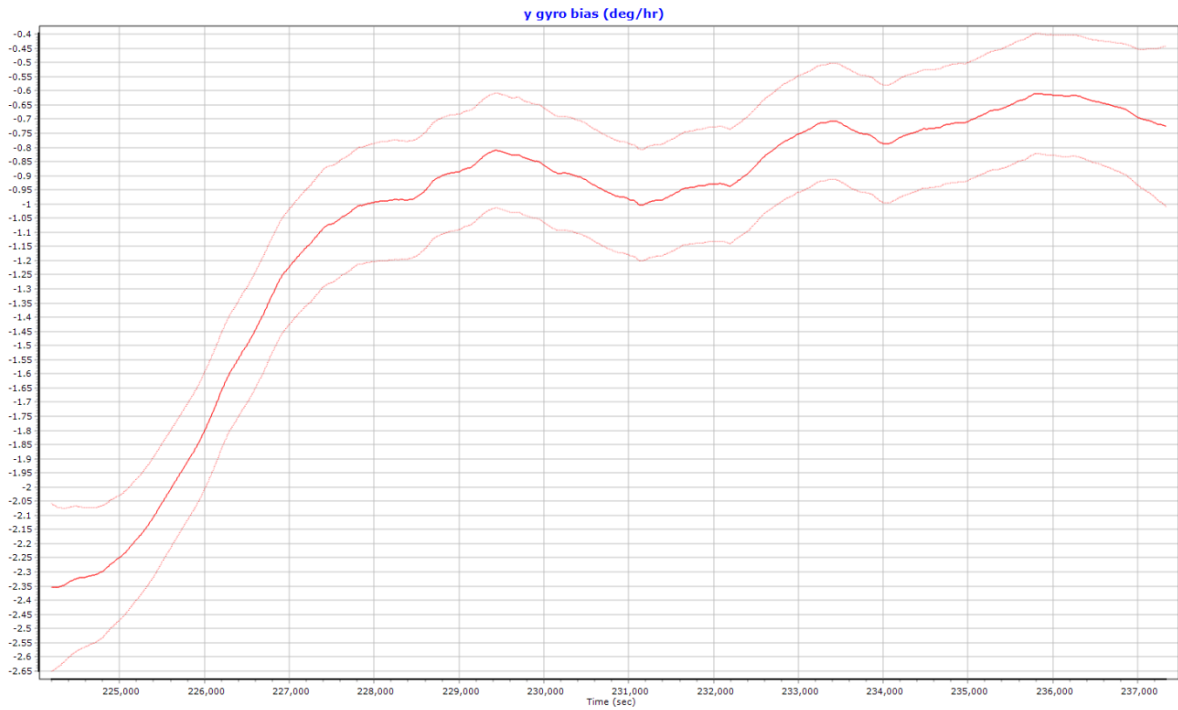
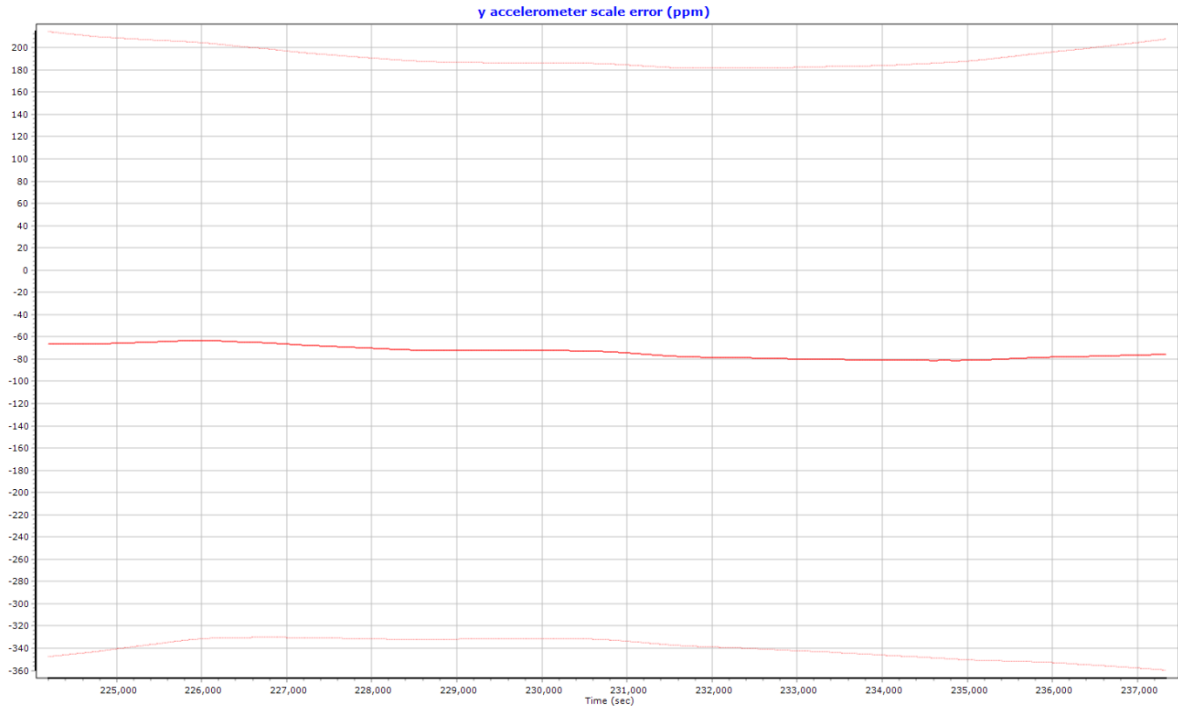


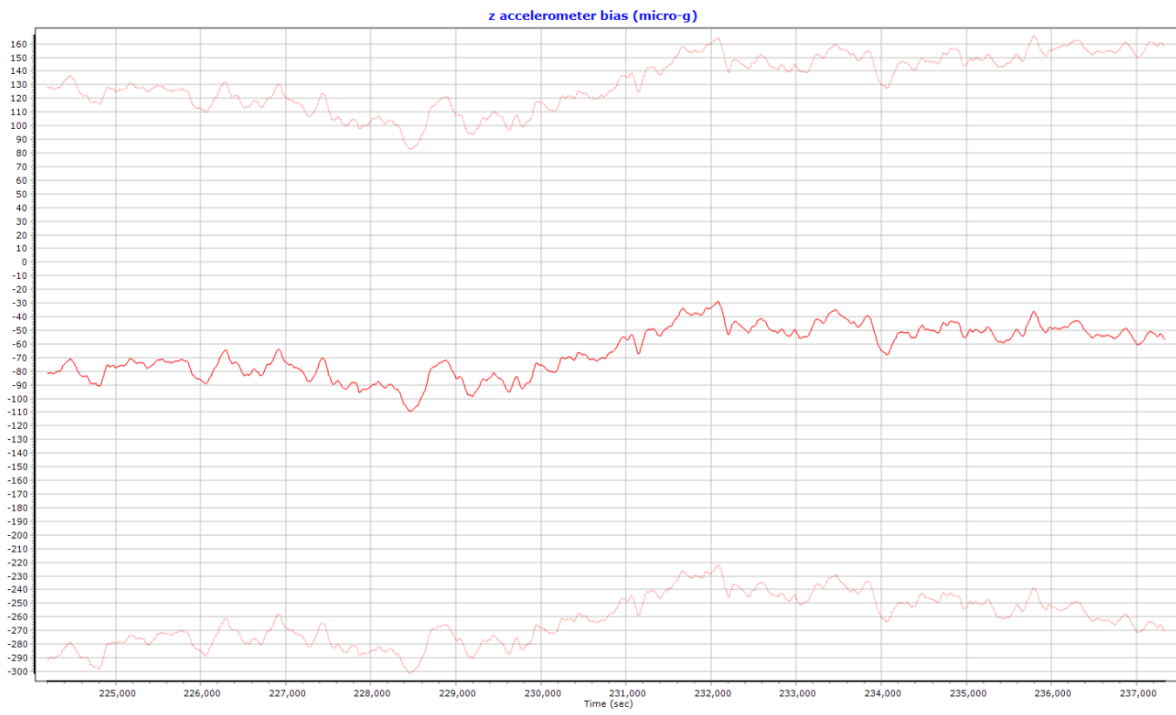
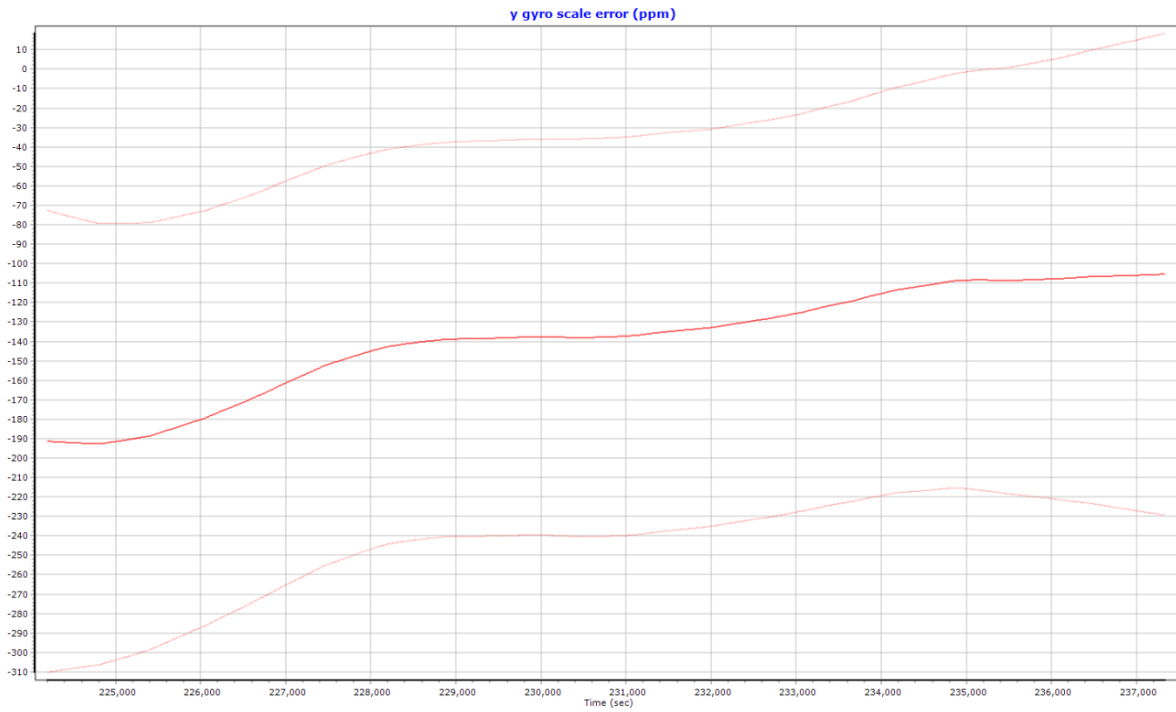


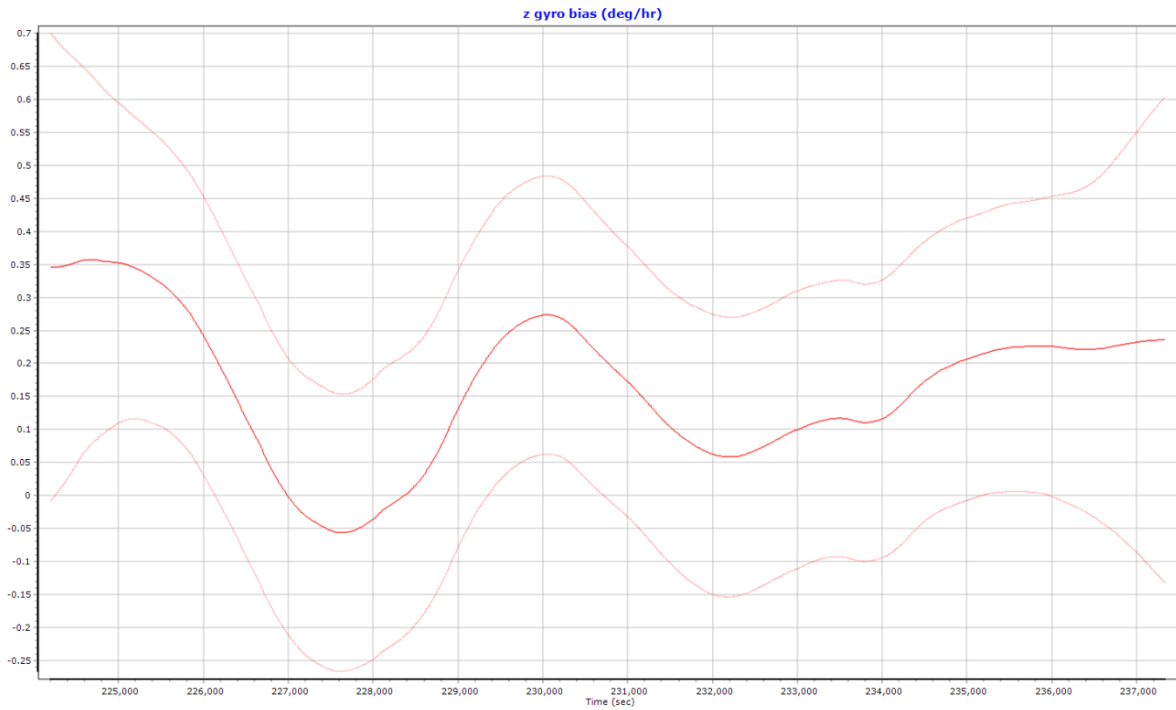
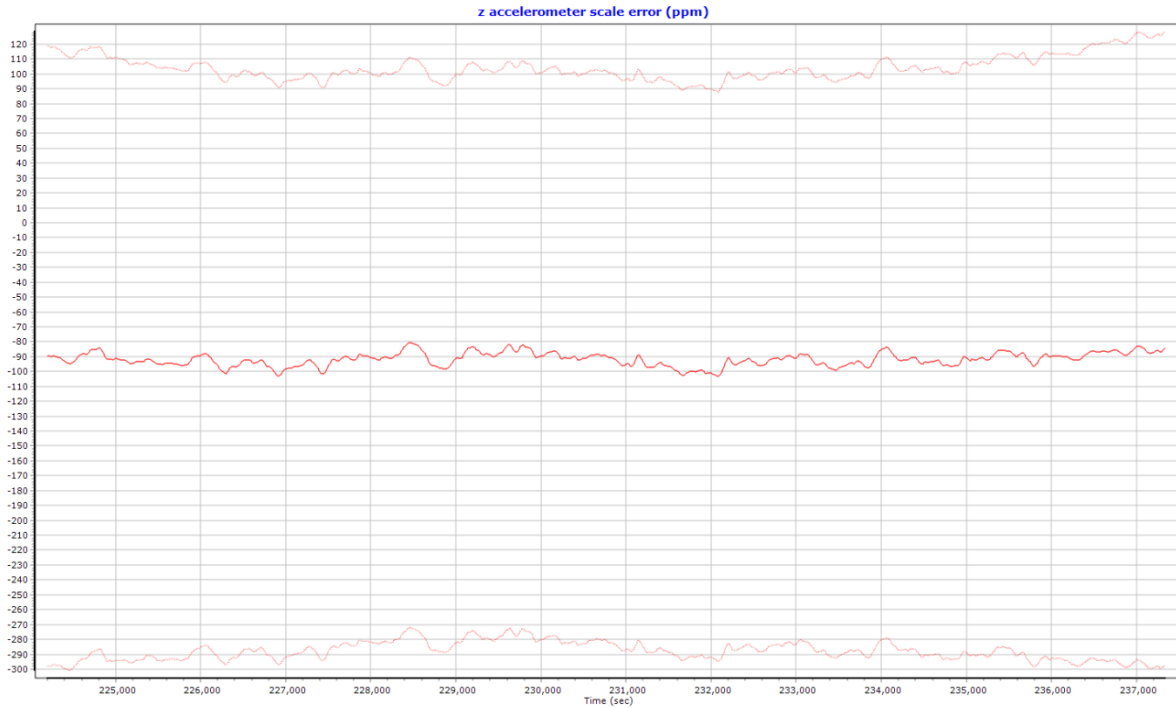


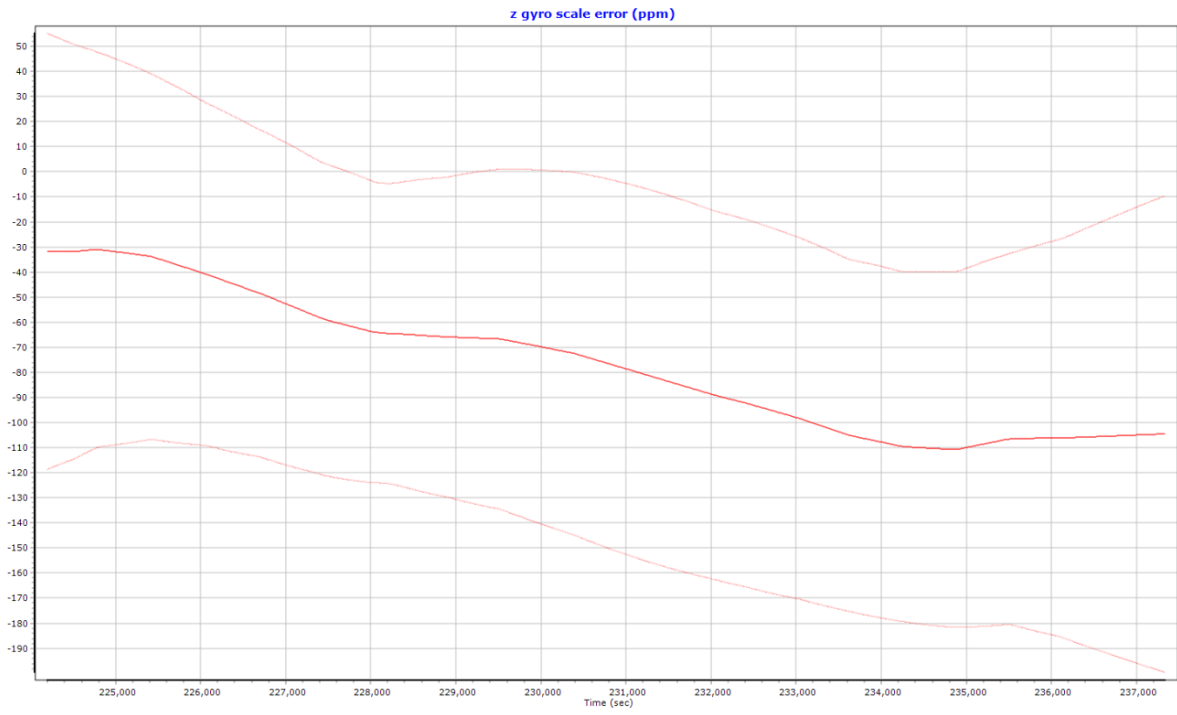




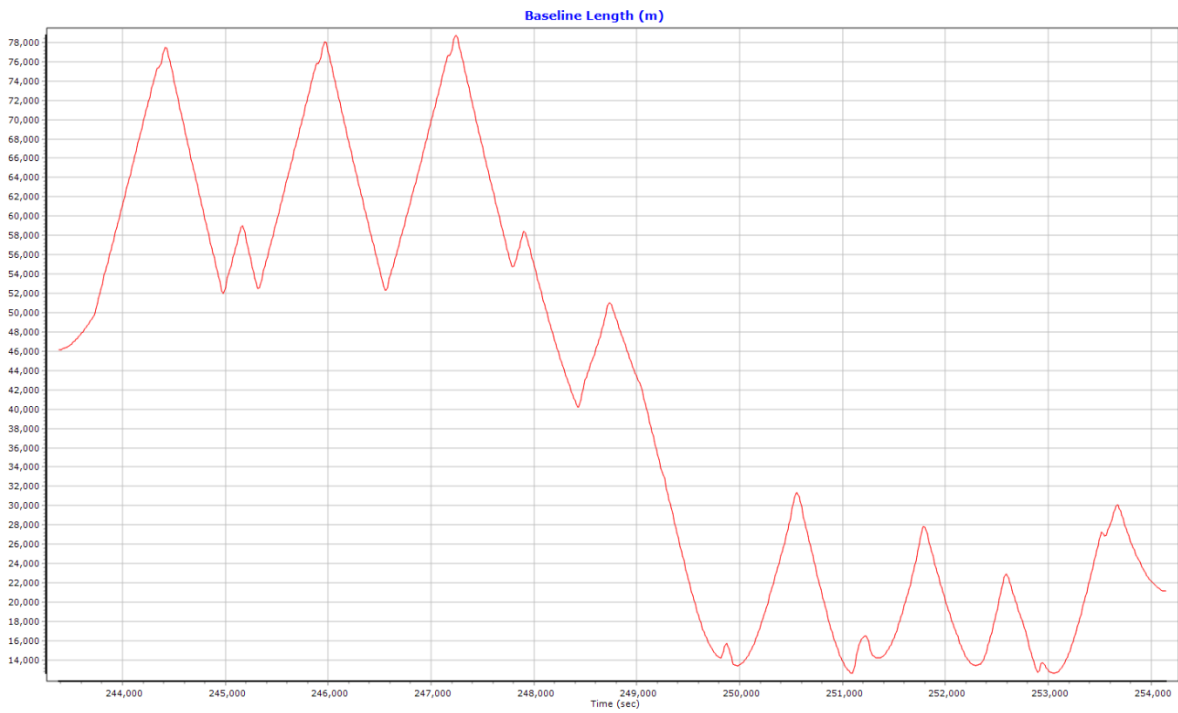
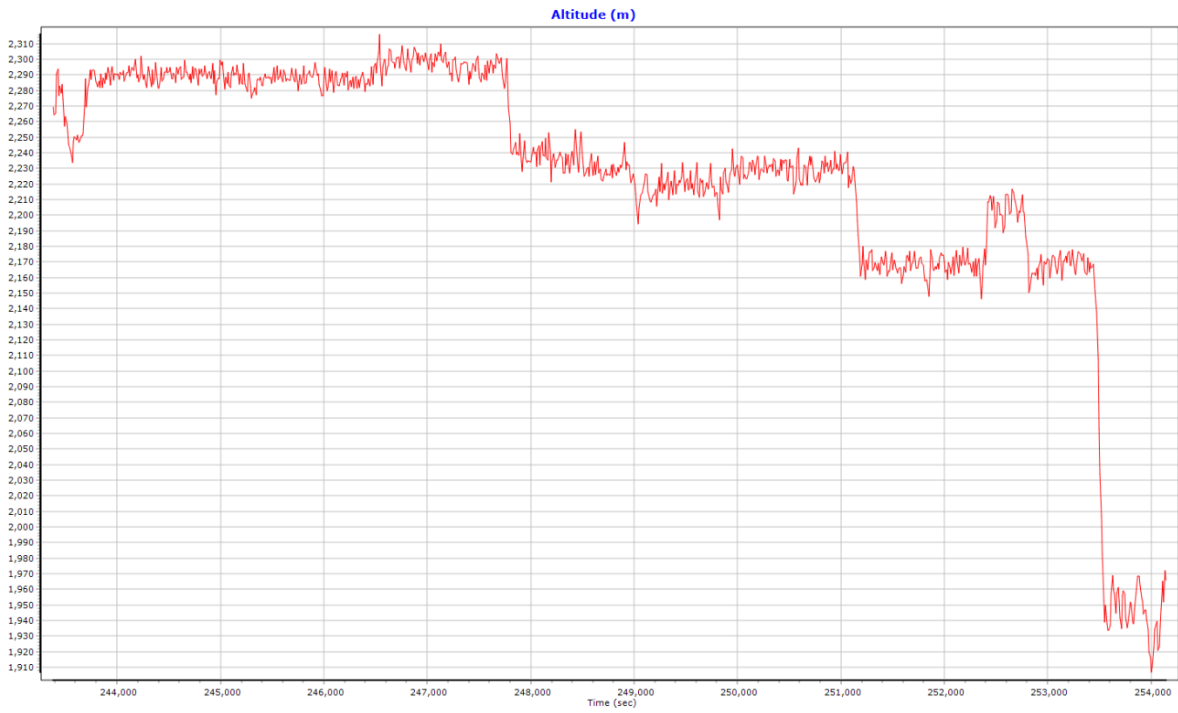


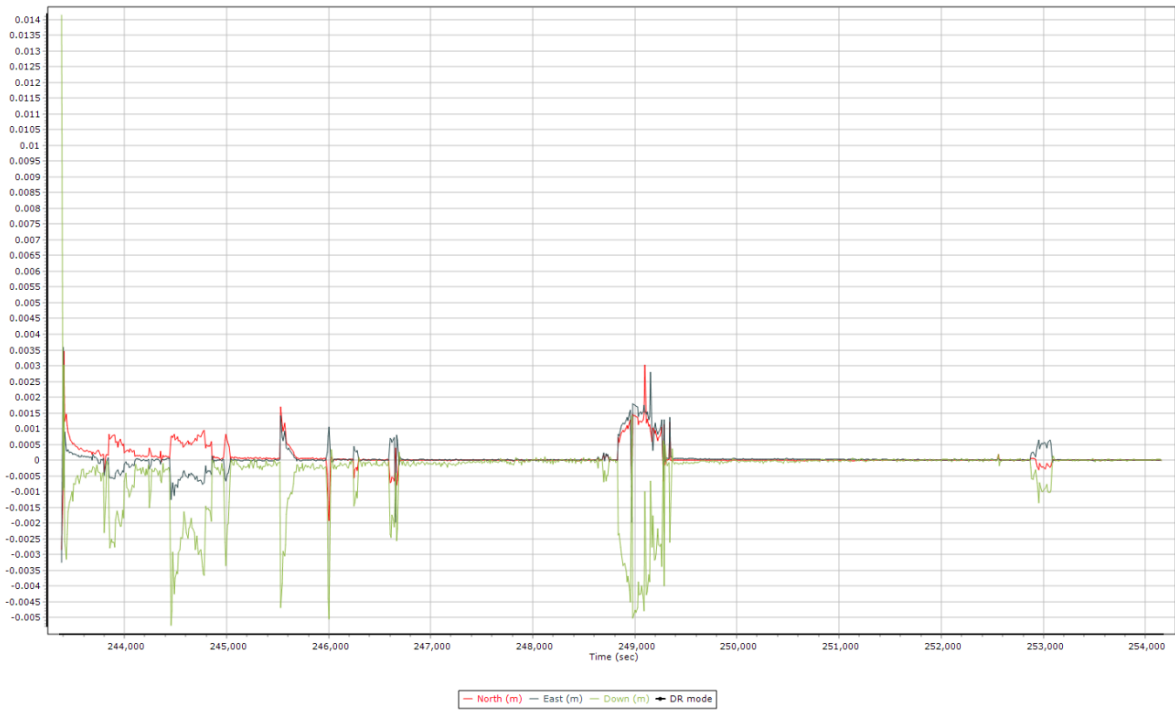
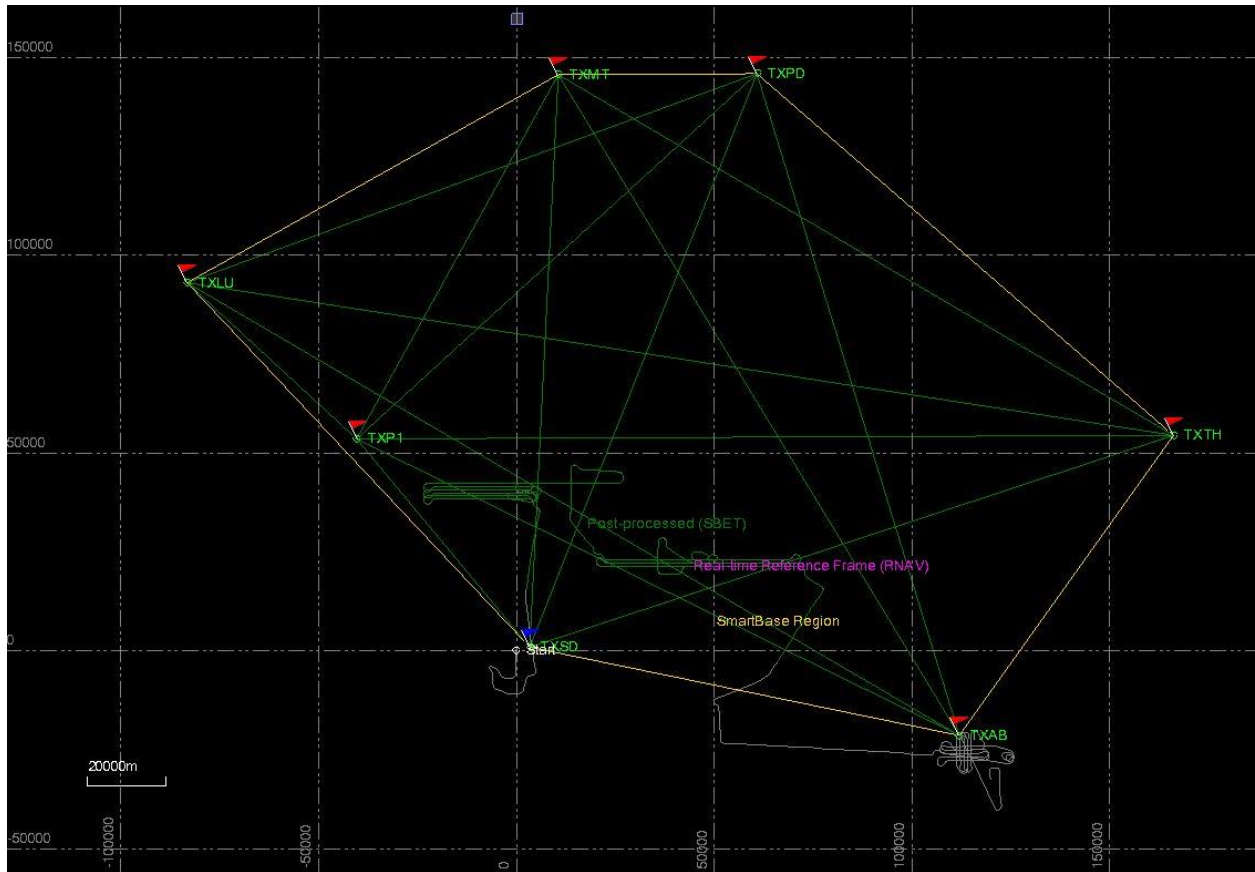






CAU18100B





Project Settings

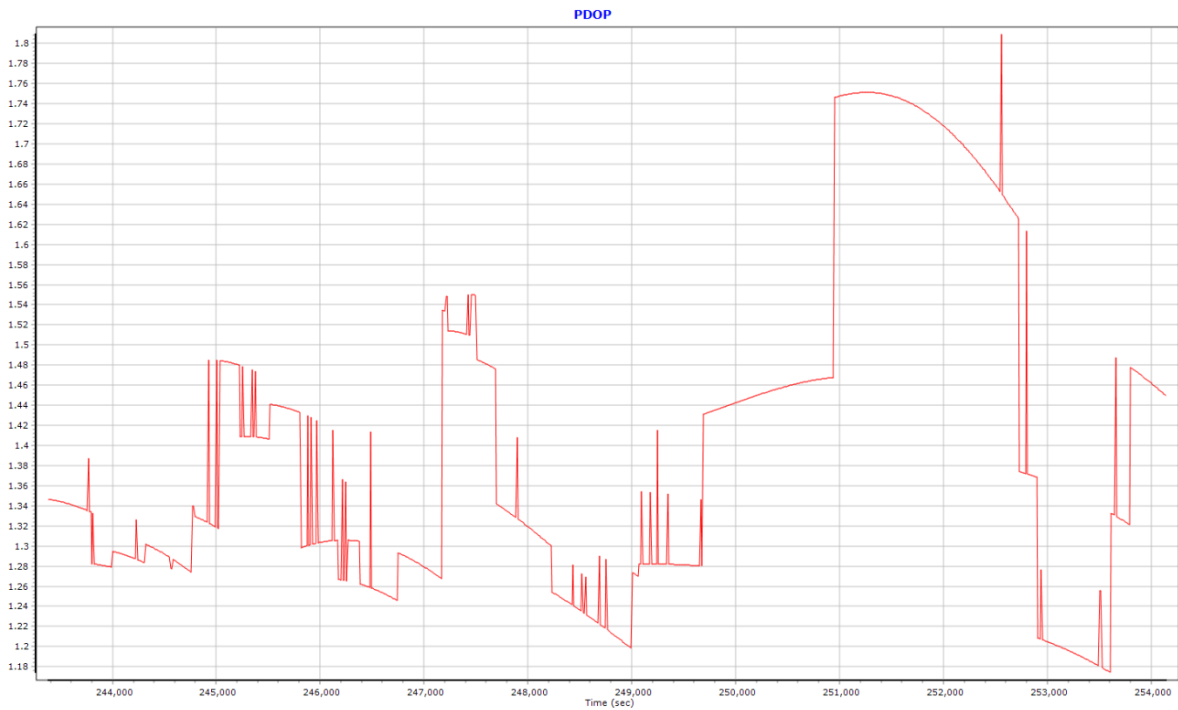
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

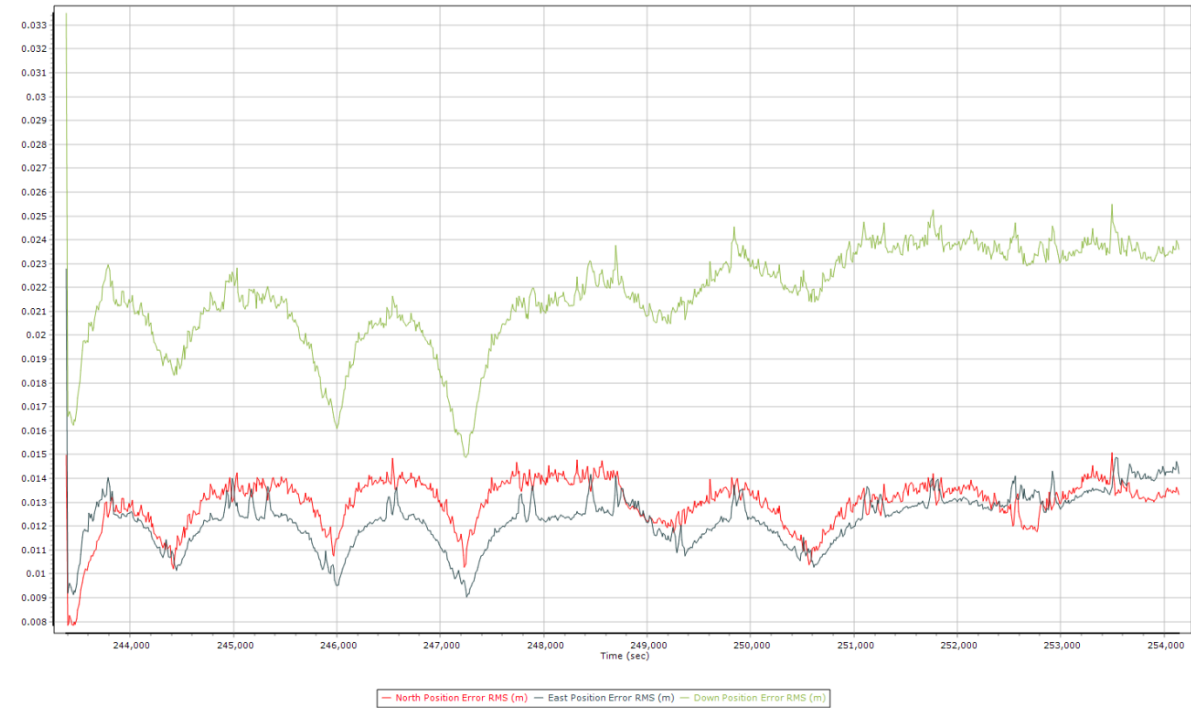
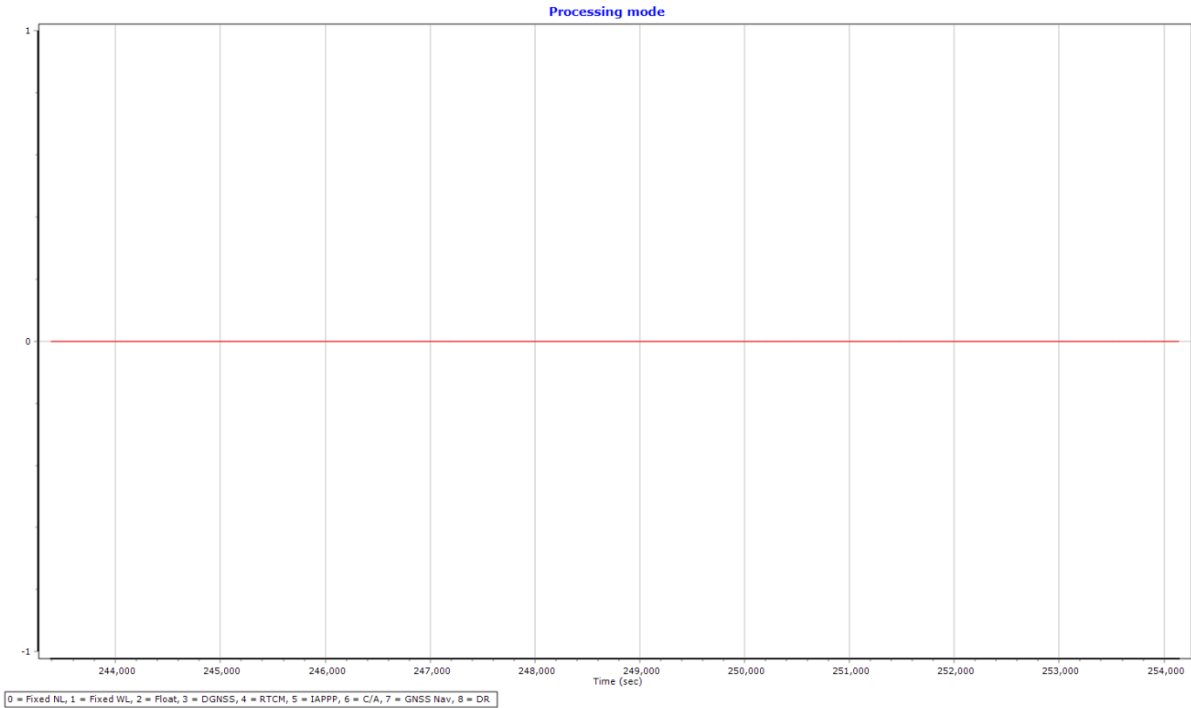
Reference to IMU Lever Arm	Reference to IMU Mounting Angles
X: 0.034 m	X: 0.000 deg
Y: 0.018 m	Y: 0.000 deg
Z: -0.210 m	Z: 180.000 deg

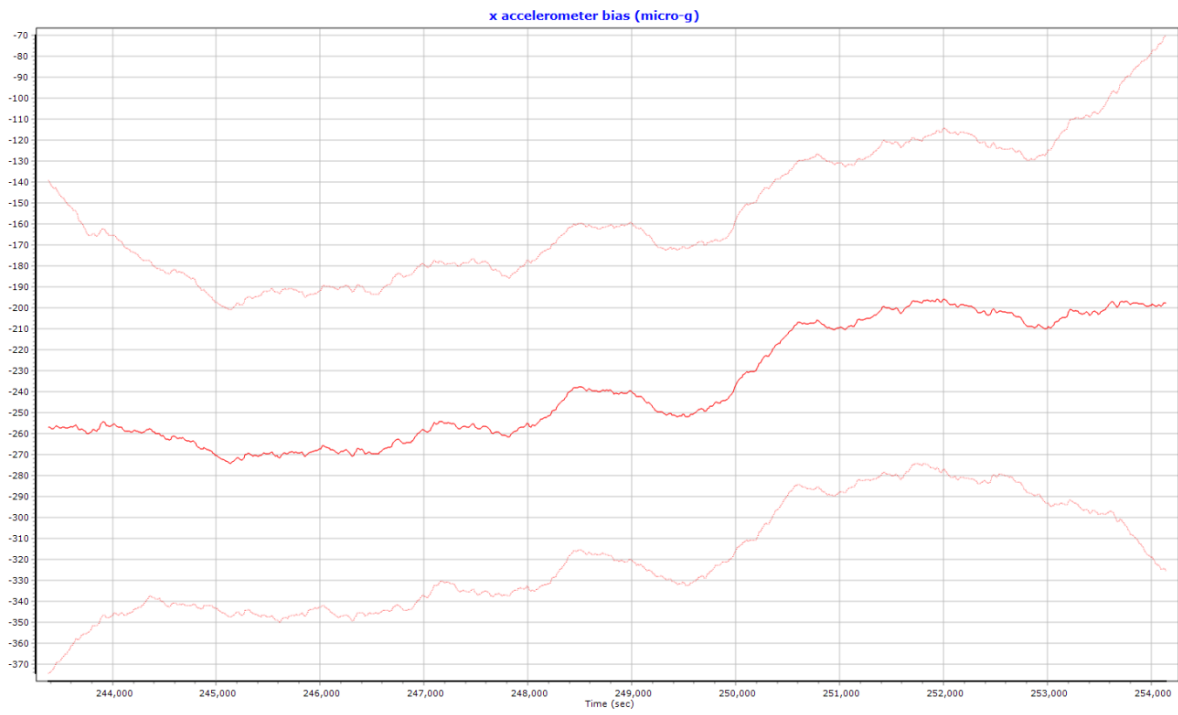
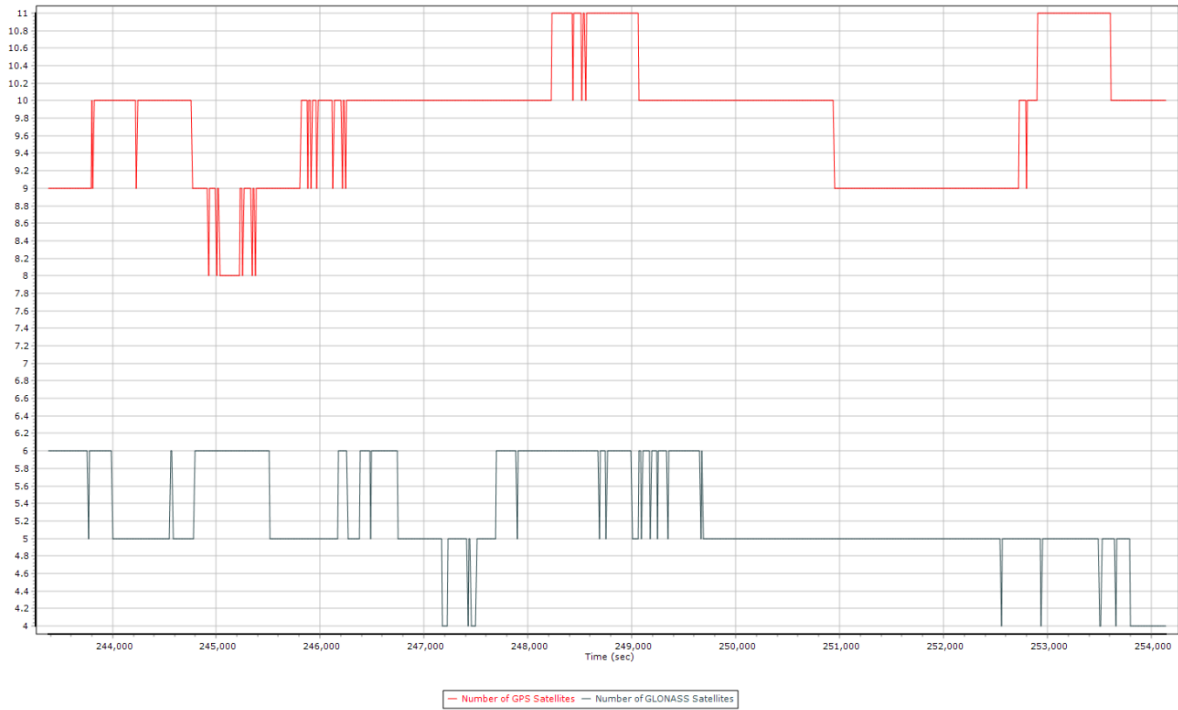
Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.174 m	X: 0.000 deg
Y: -0.025 m	Y: 0.000 deg
Z: -0.968 m	Z: 0.000 deg

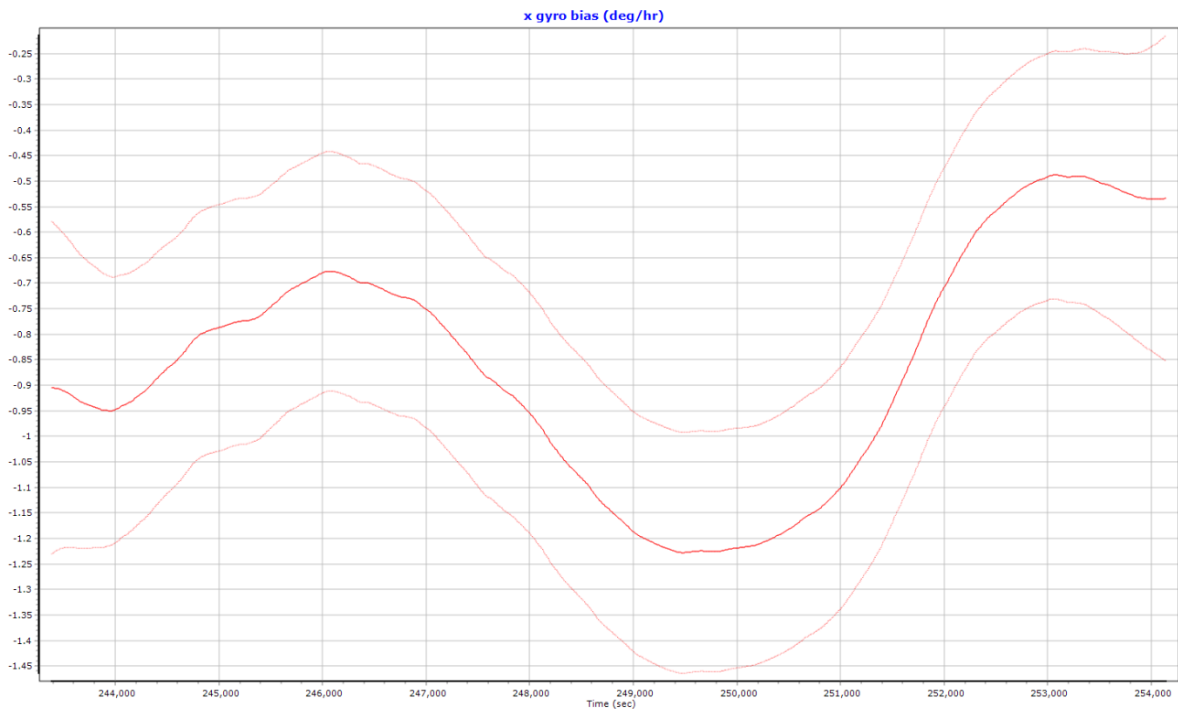
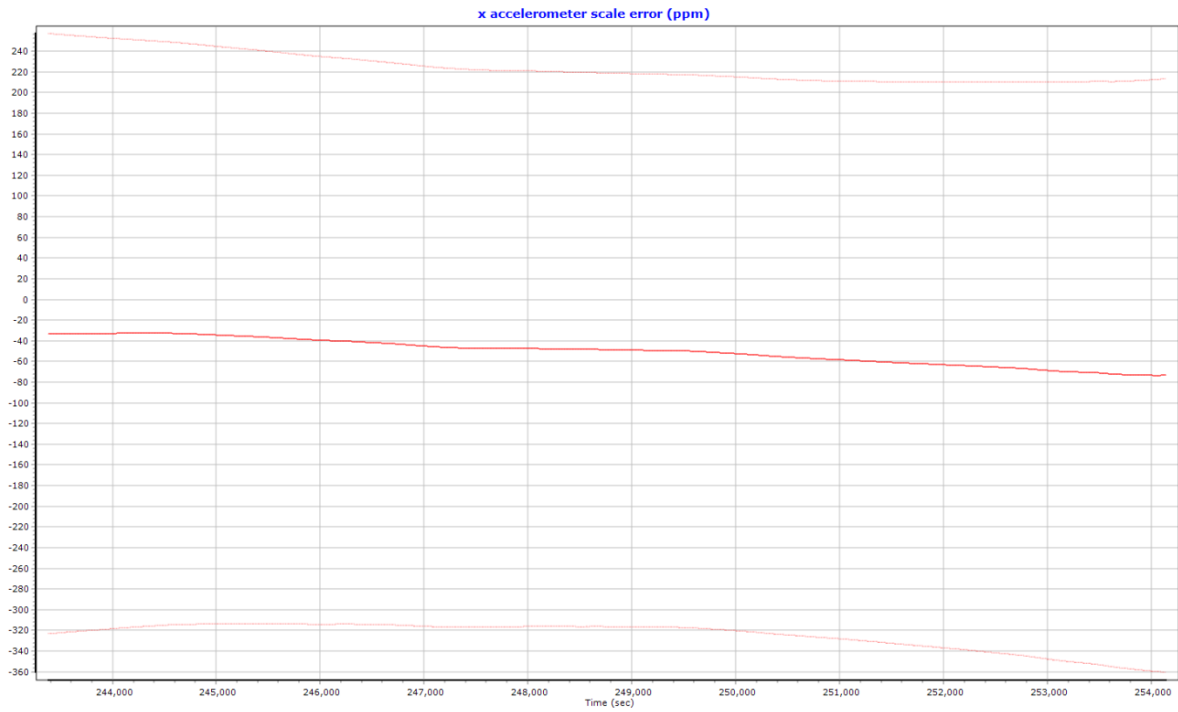
Standard Deviation: <3cm 10cm 50cm 1m 10m

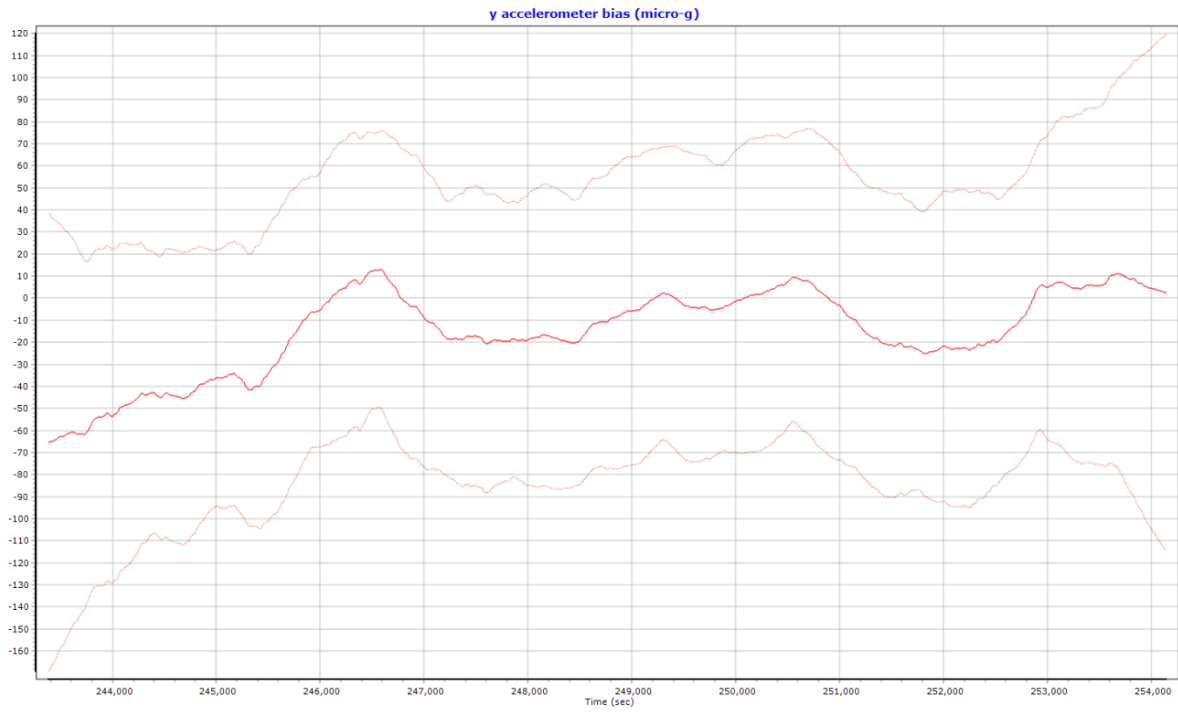
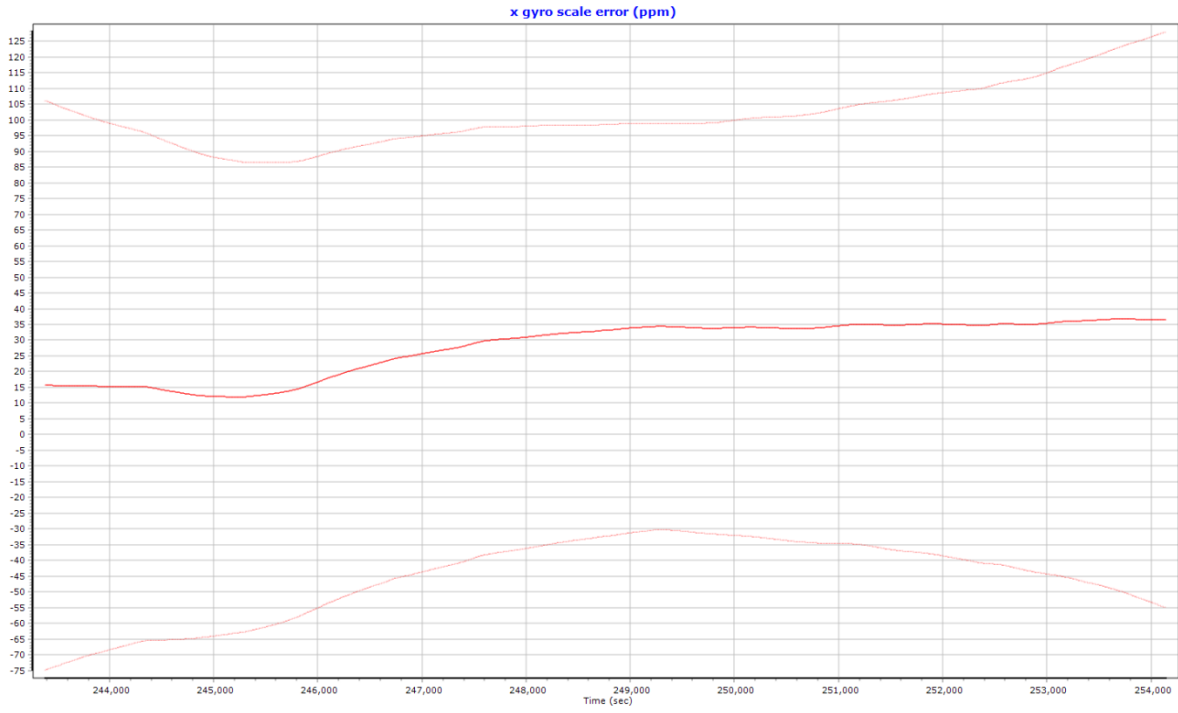
OK Cancel

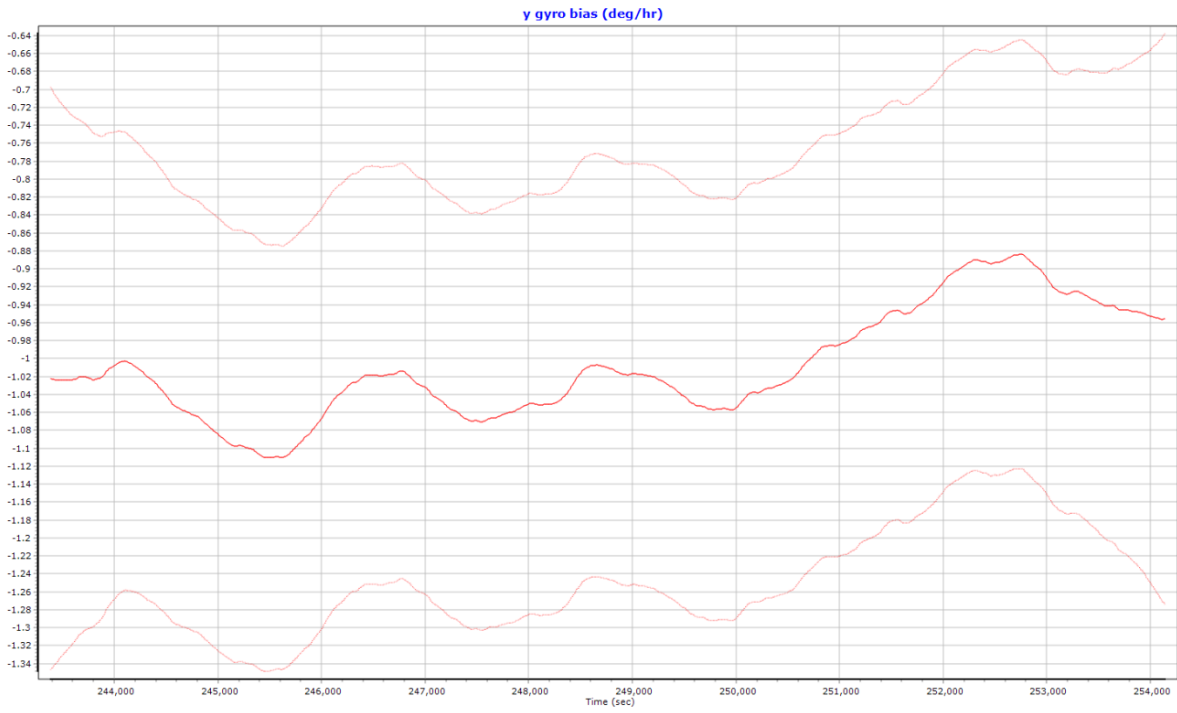
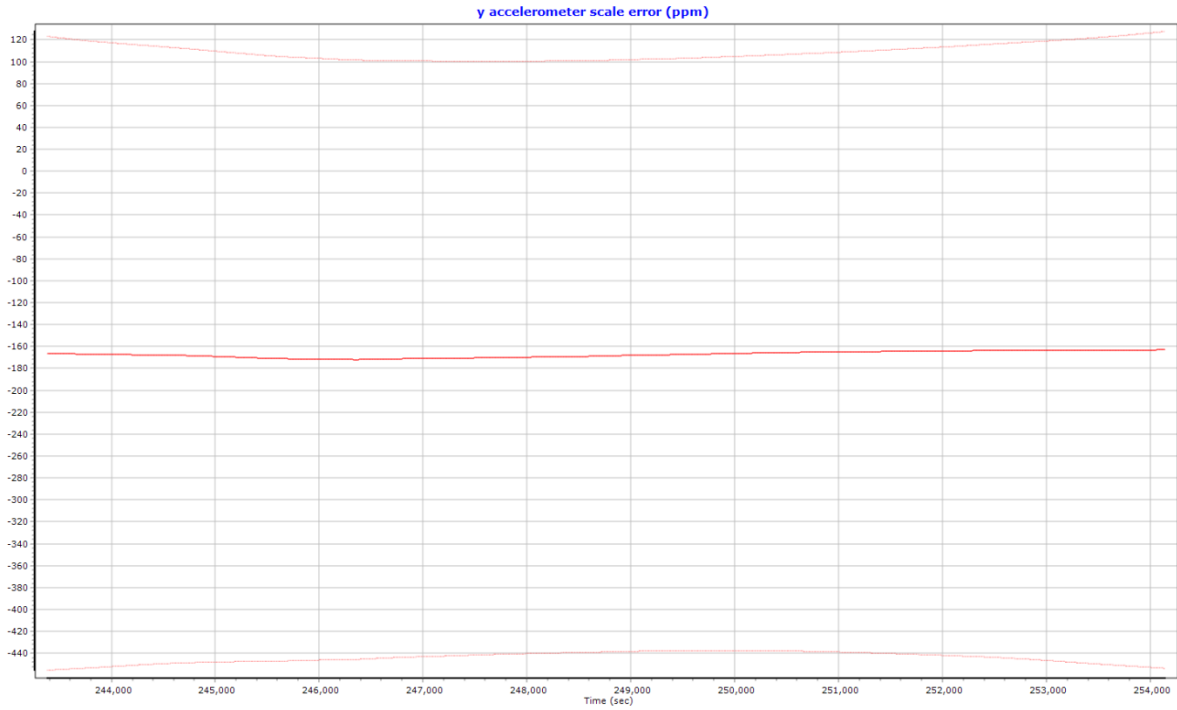


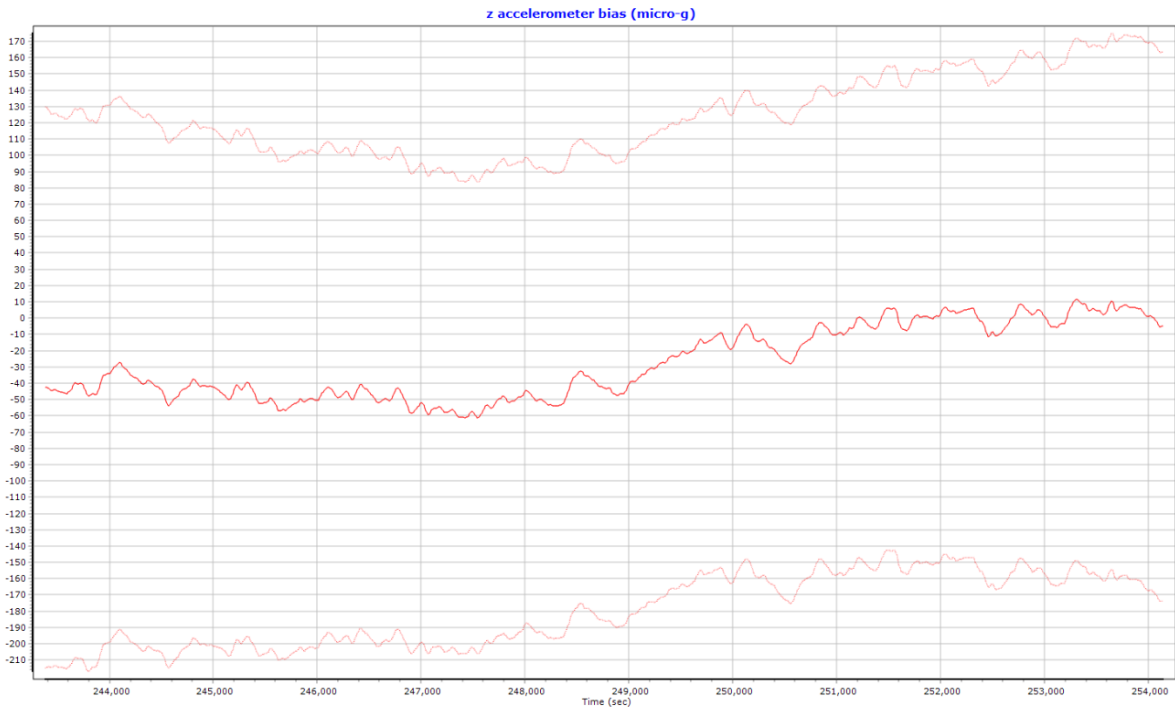
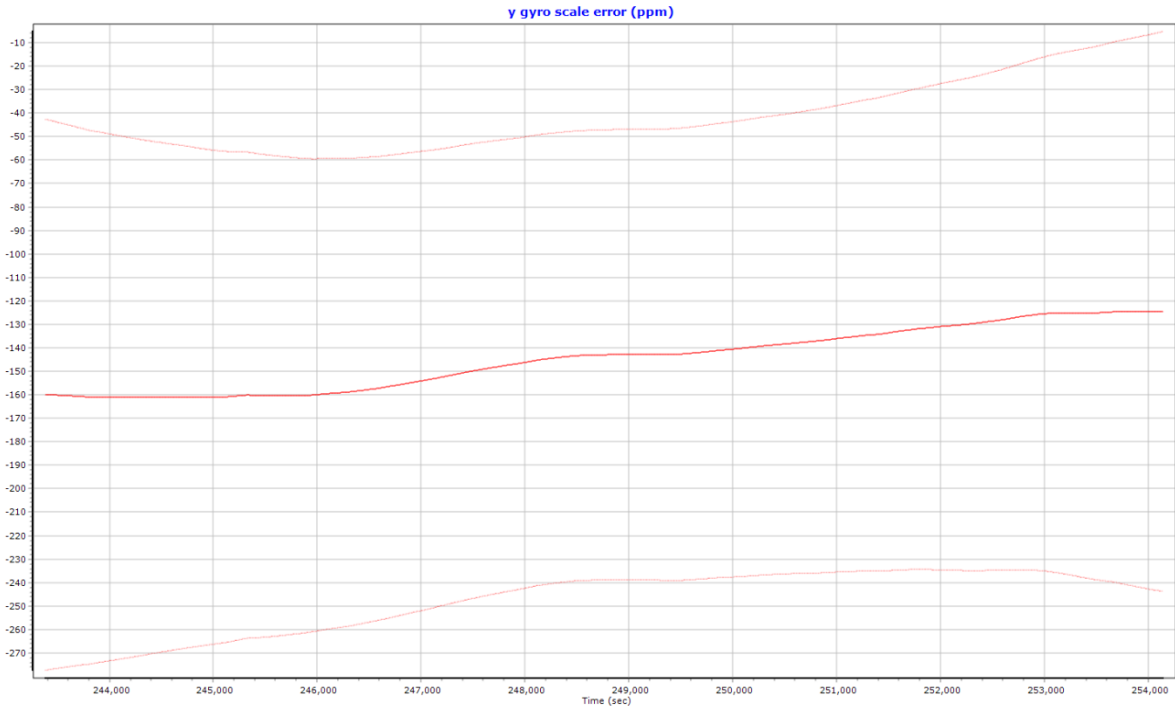


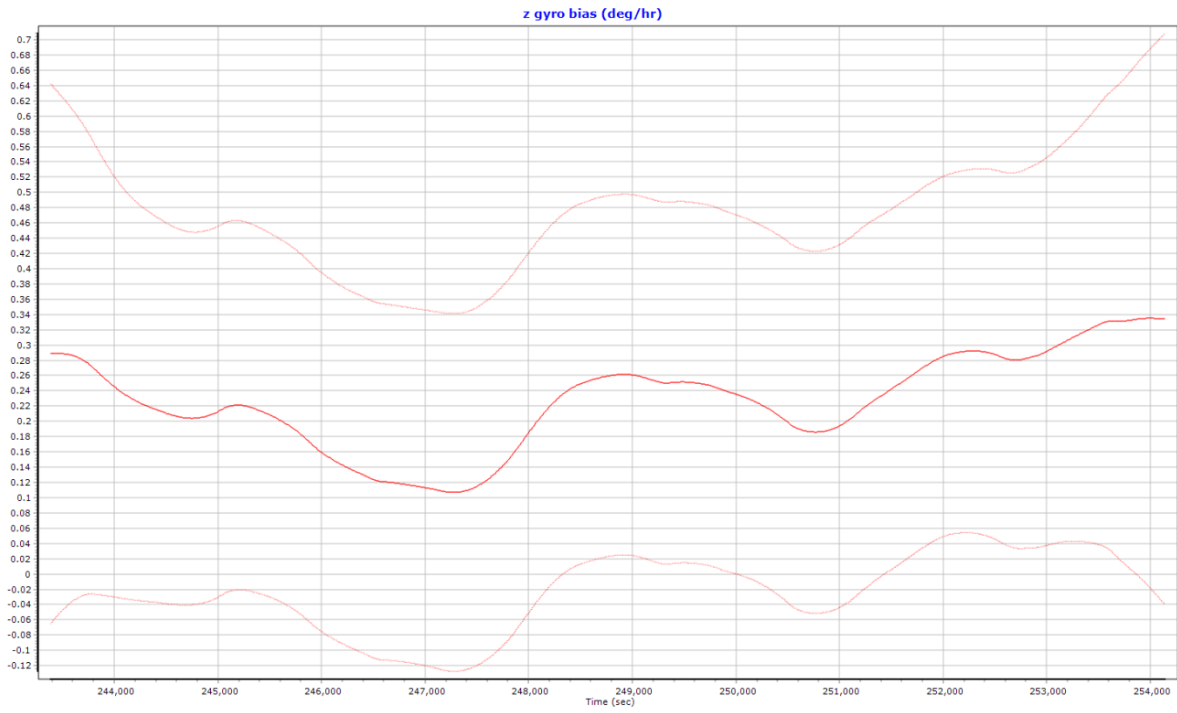
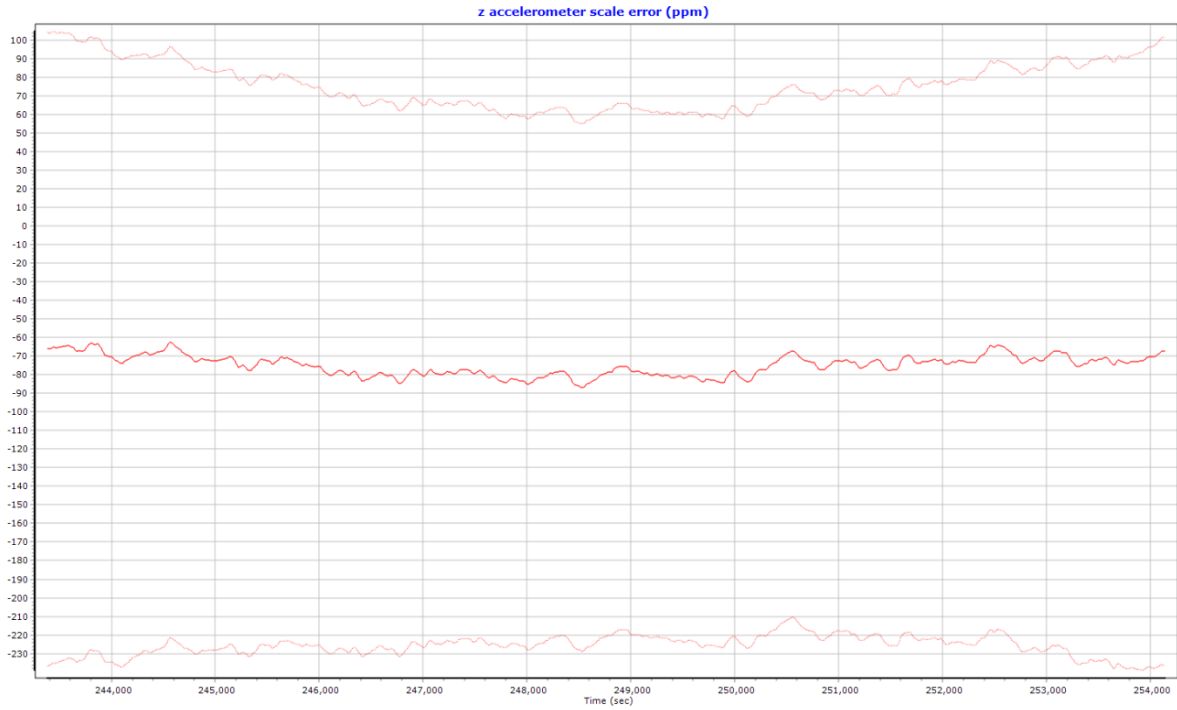


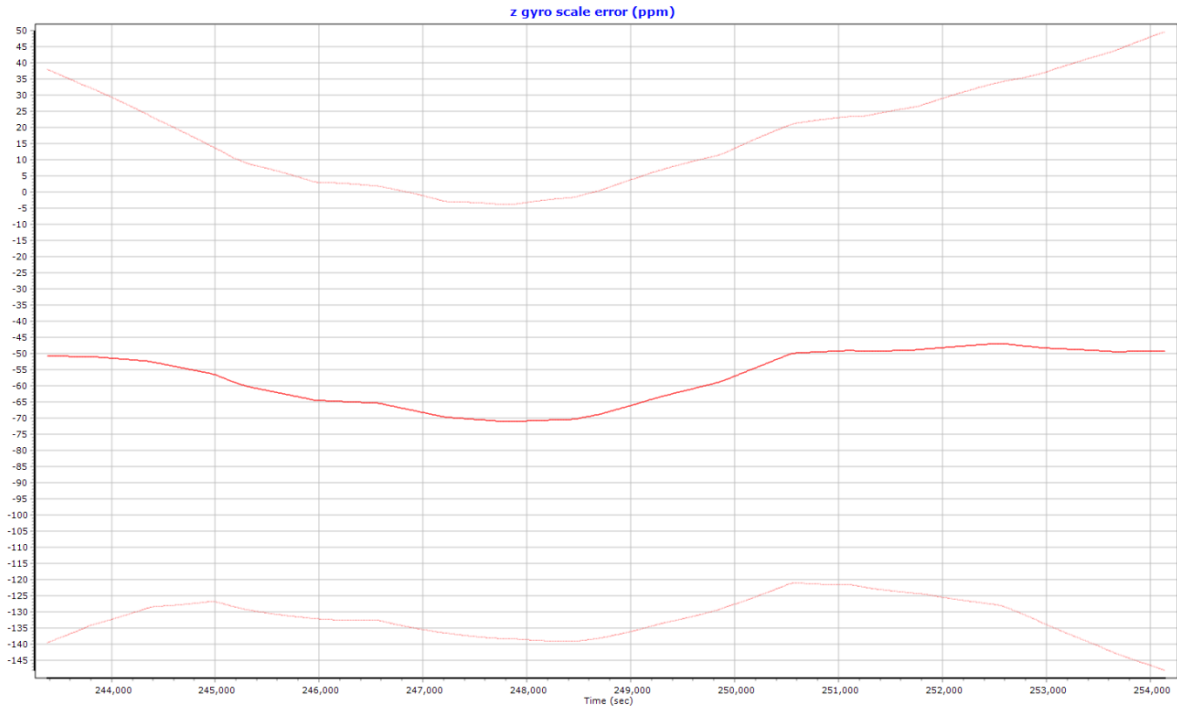




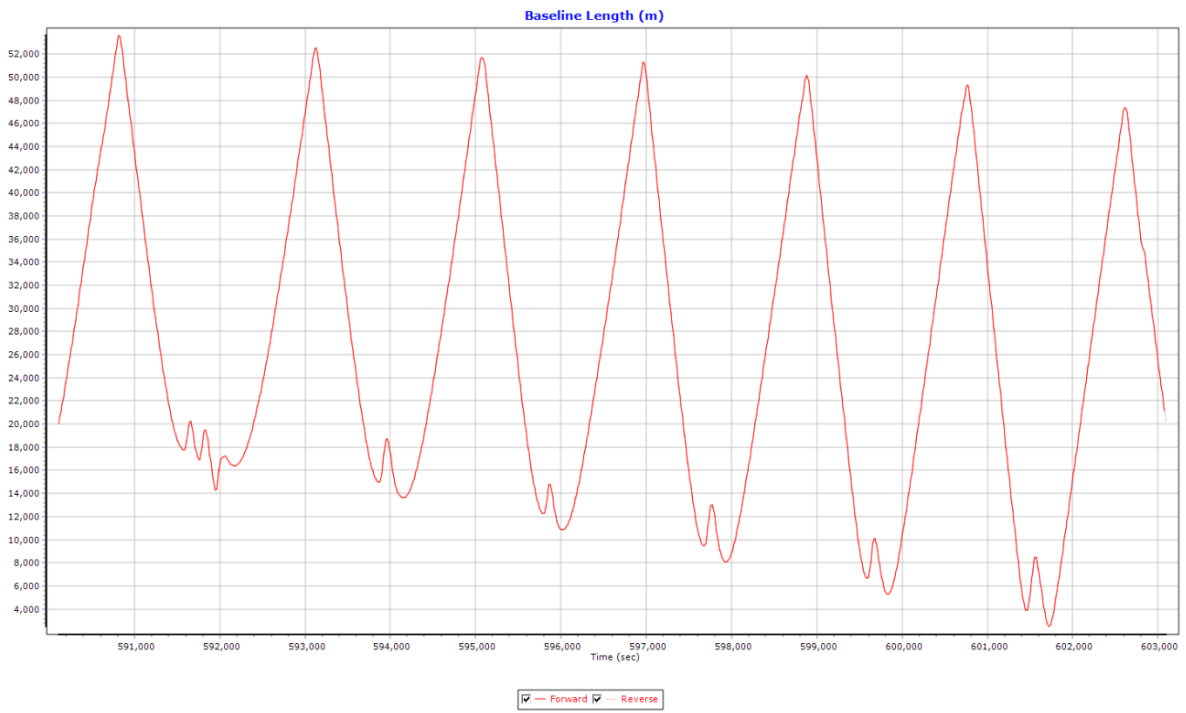
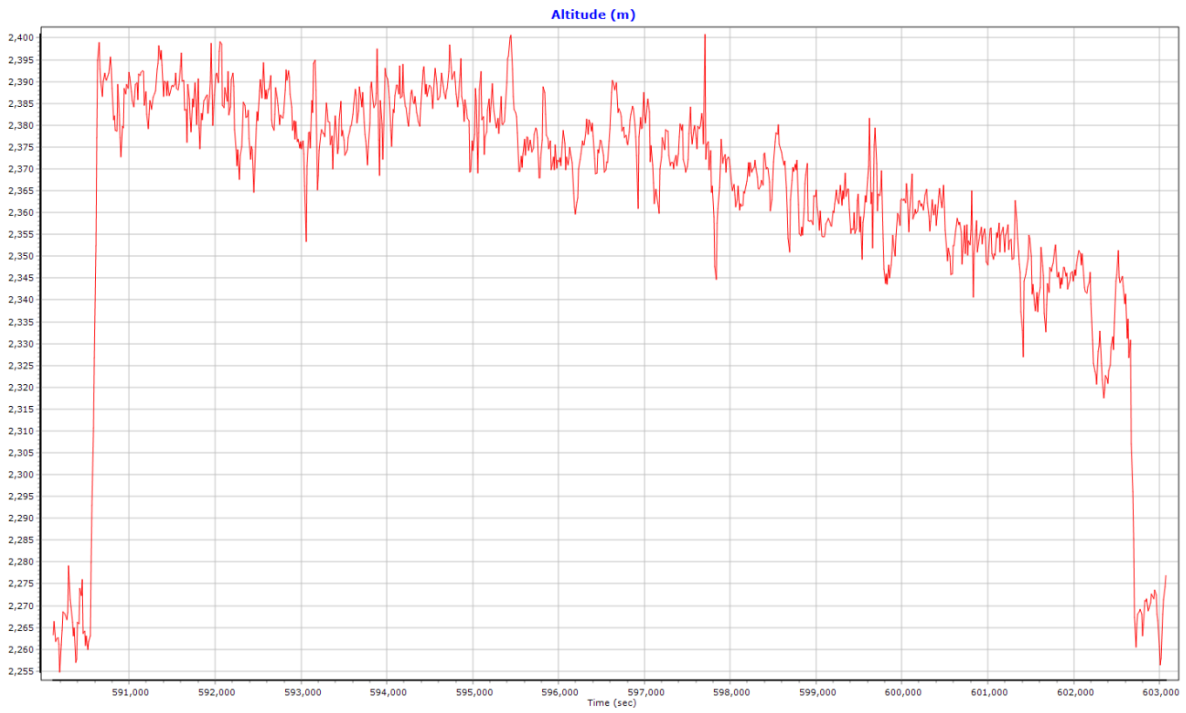


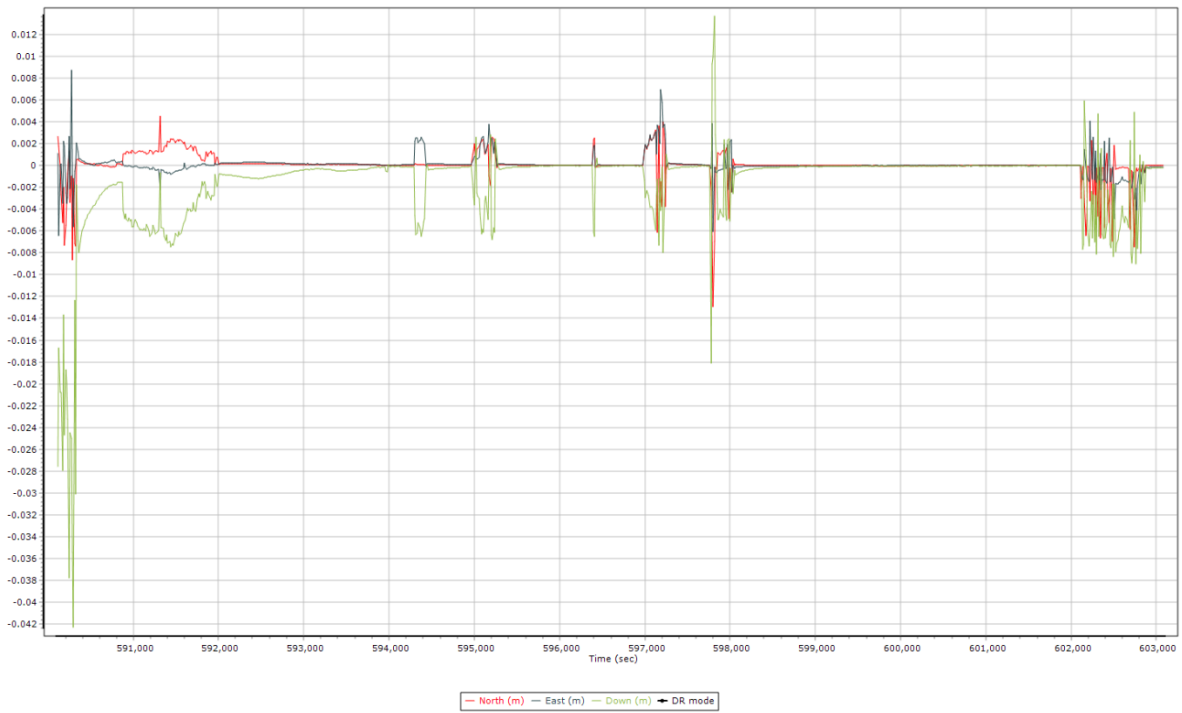
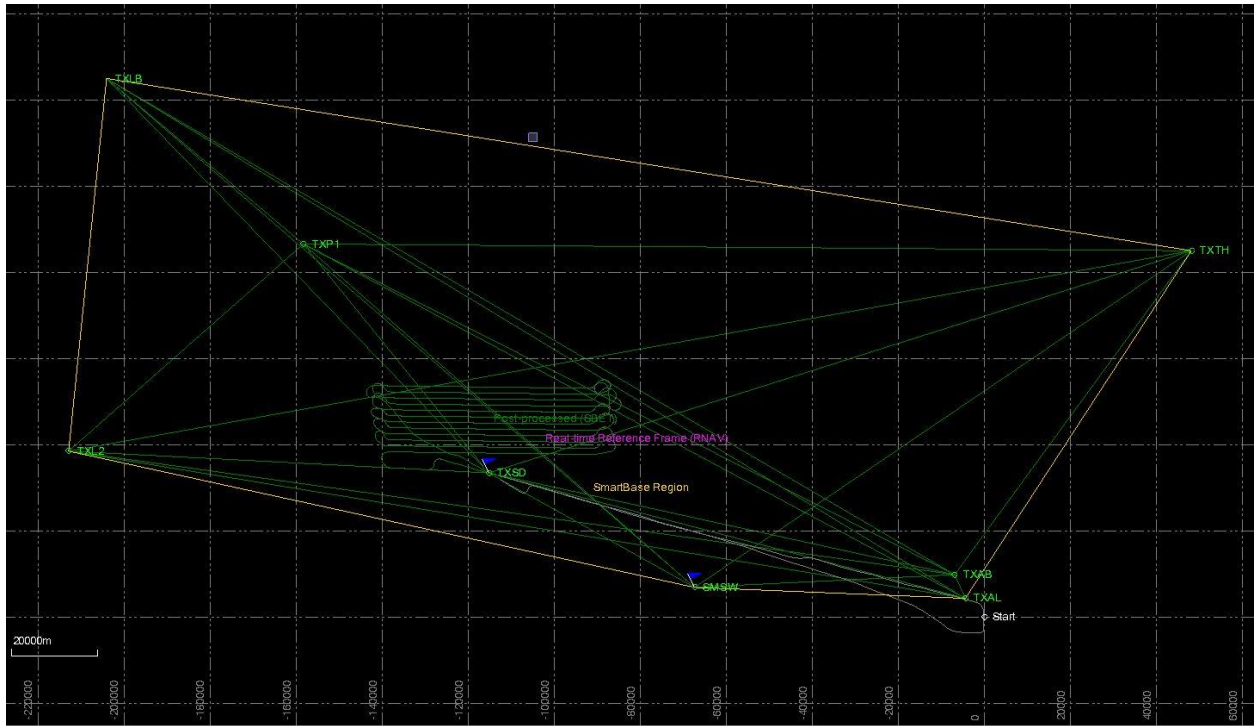






RBV18048A





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	0.000 m
Y	0.000 m
Z	0.000 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	-0.031 m
Y	0.004 m
Z	-0.611 m

Aircraft to Stabilized Mount Mounting Angles

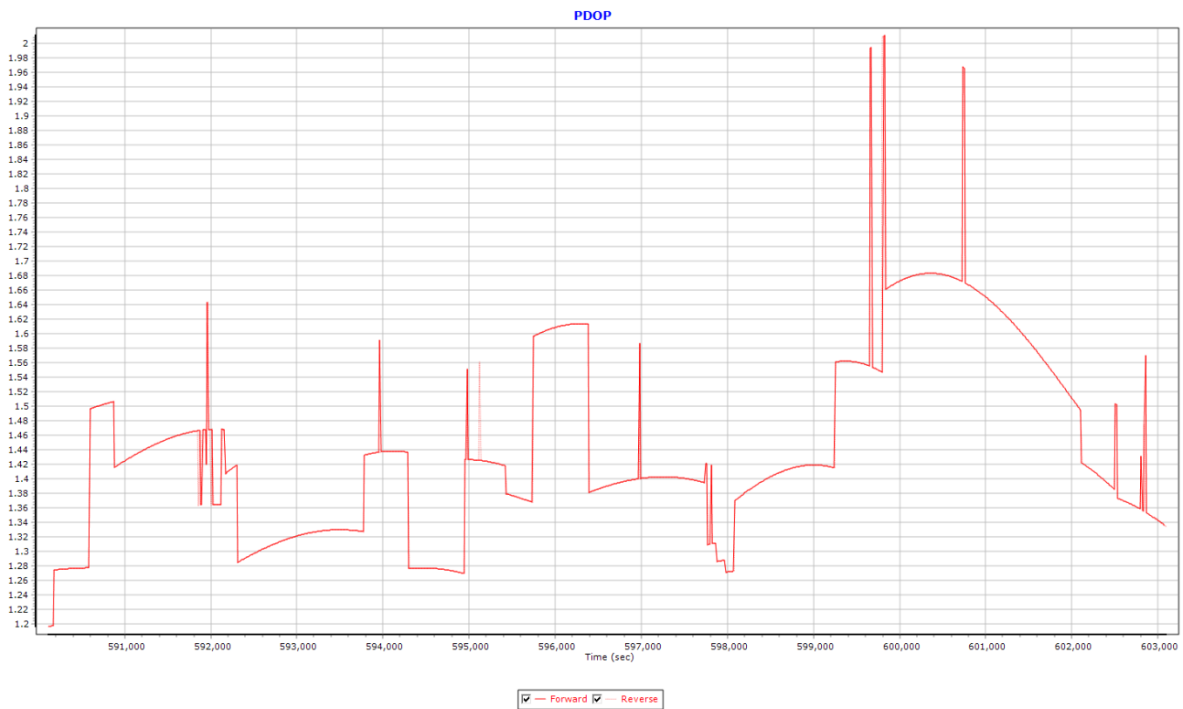
X	0.000 deg
Y	0.000 deg
Z	0.000 deg

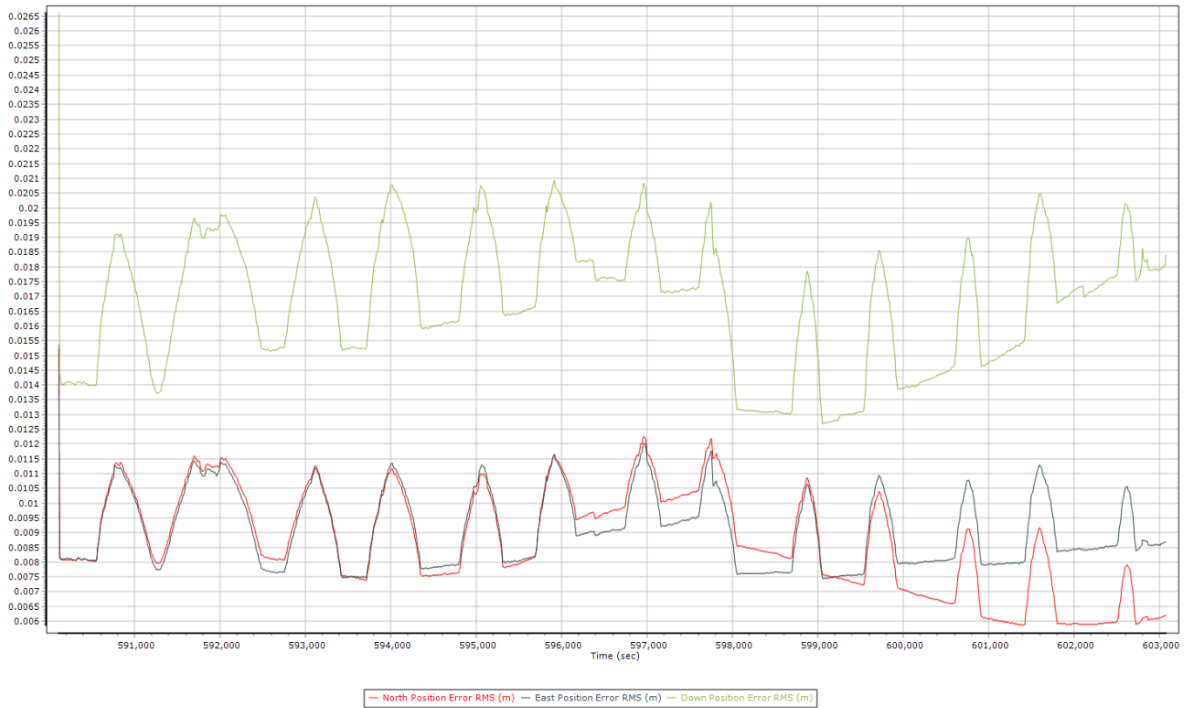
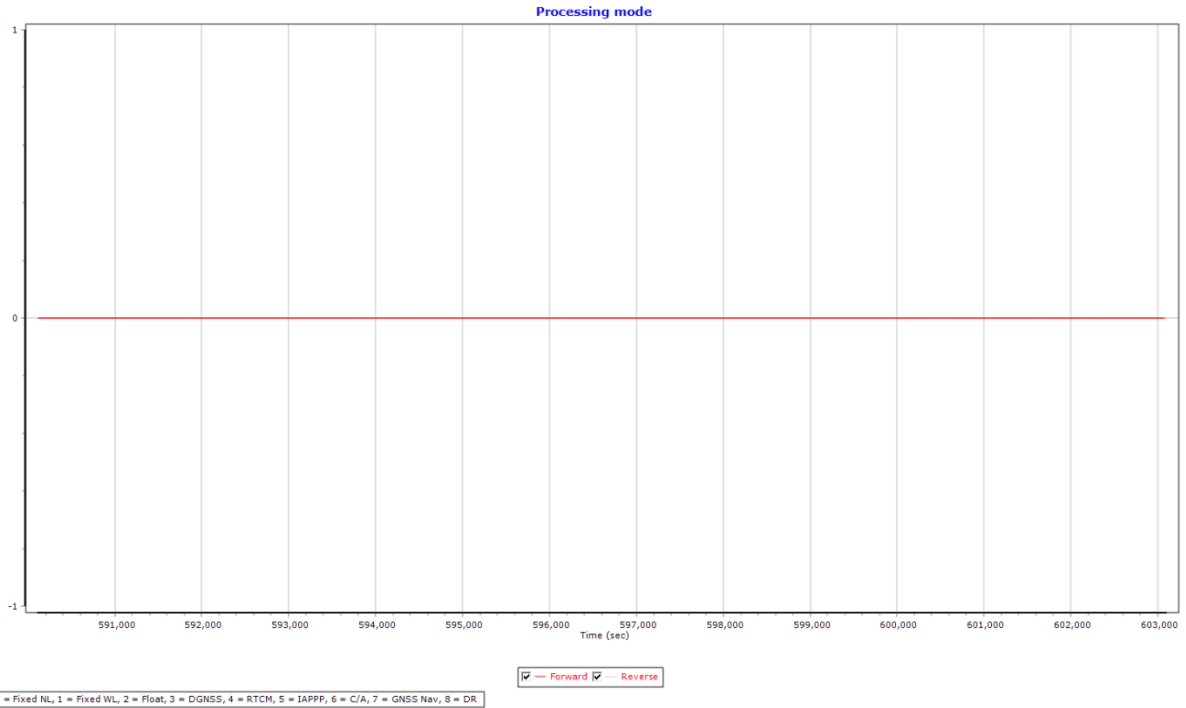
Standard Deviation

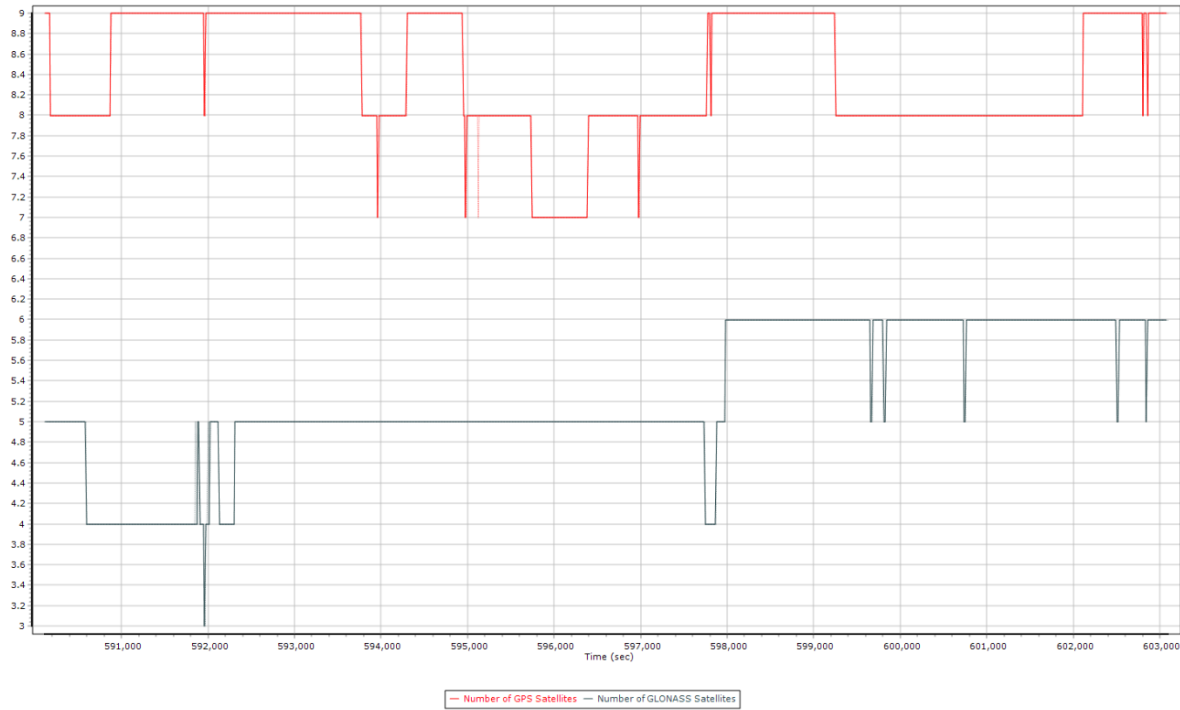
<3cm 10cm 50cm 1m 10m

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

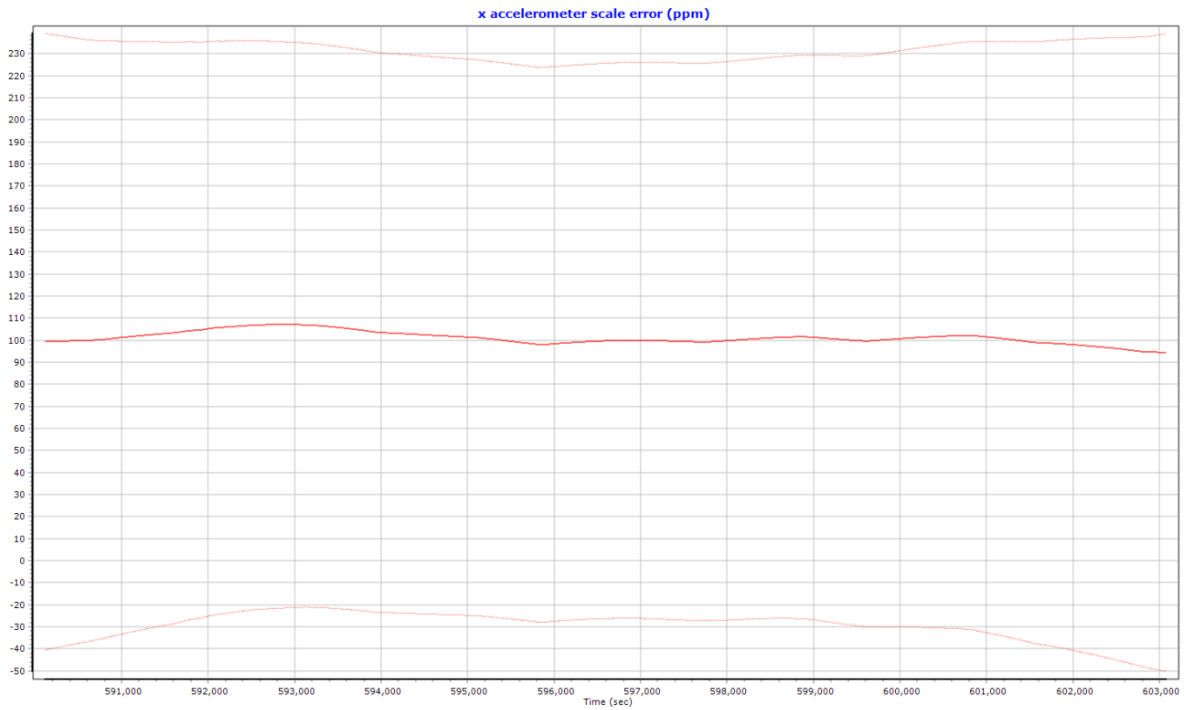
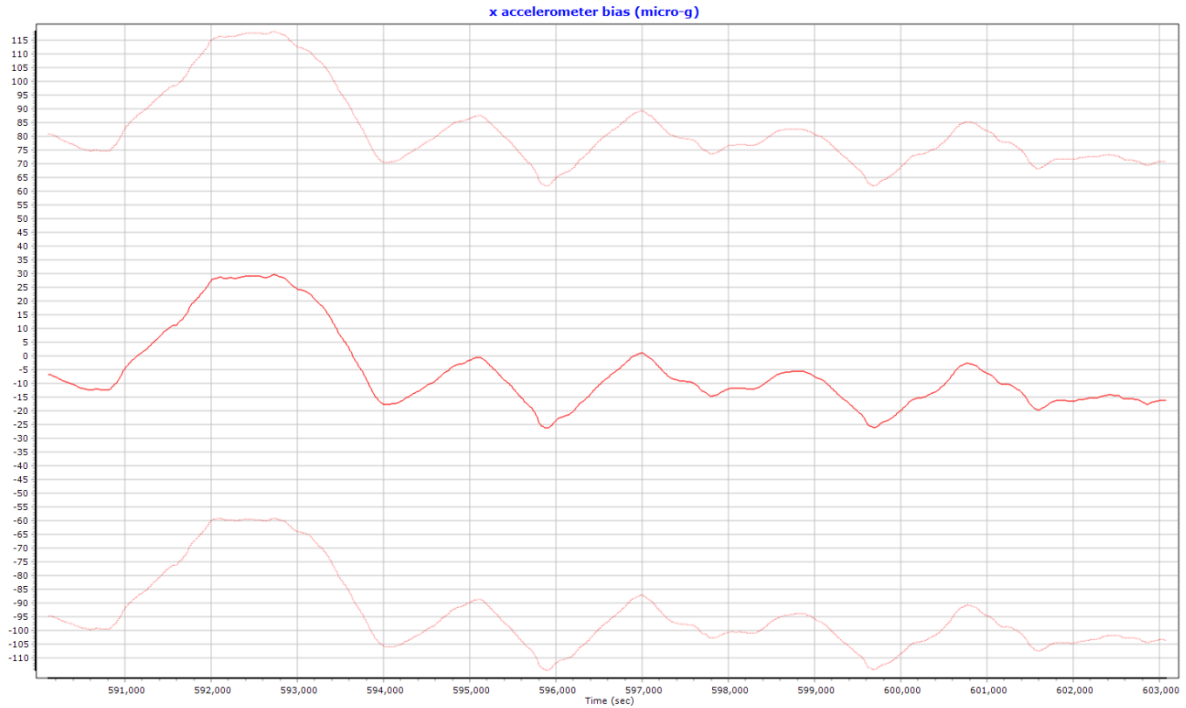
Start: 590111.884
 End: 603094.897

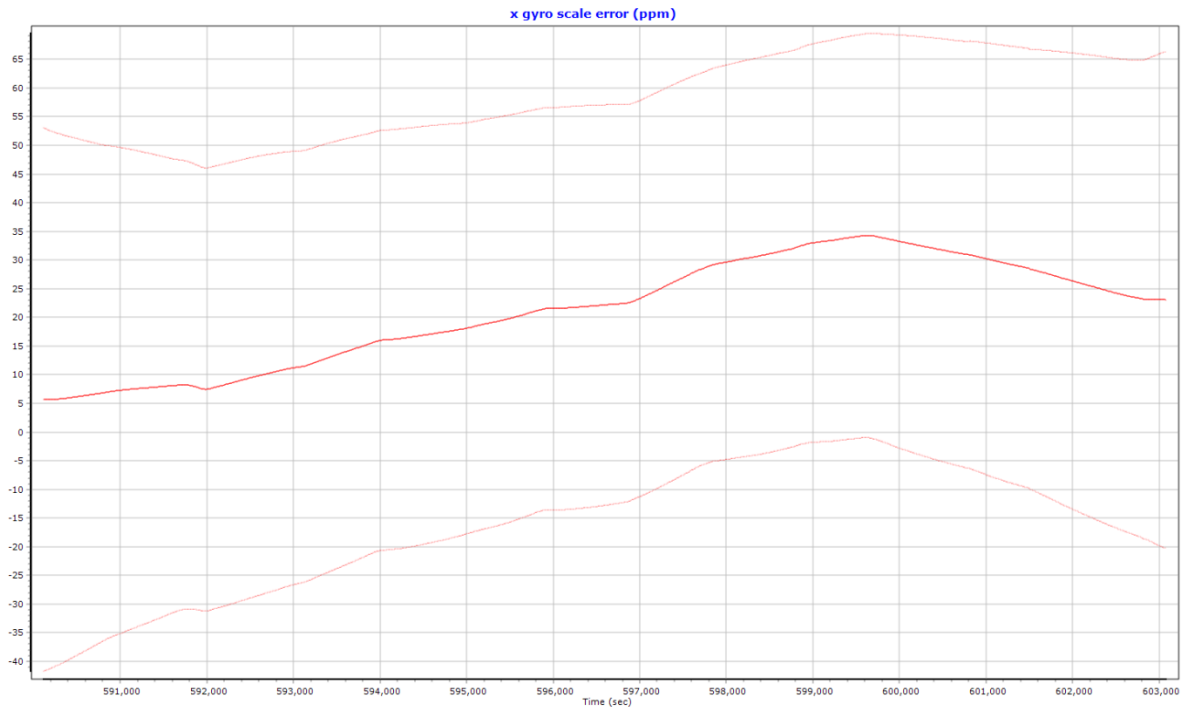
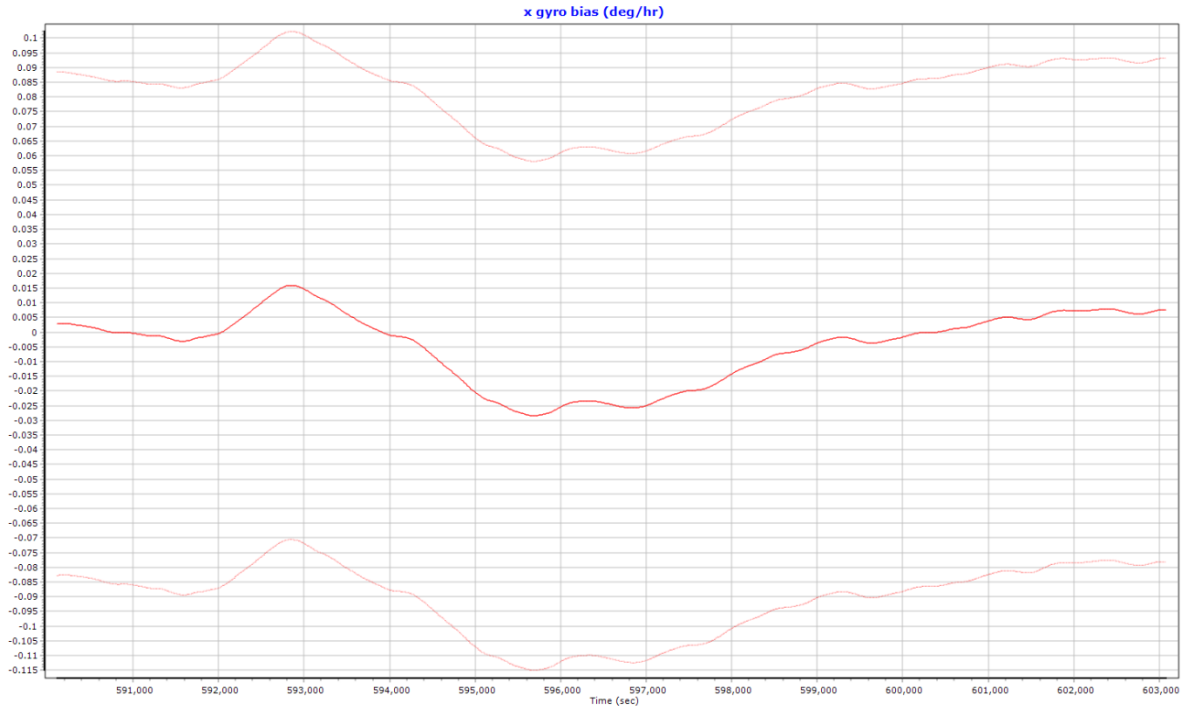
Entire time interval
 Seconds of start week

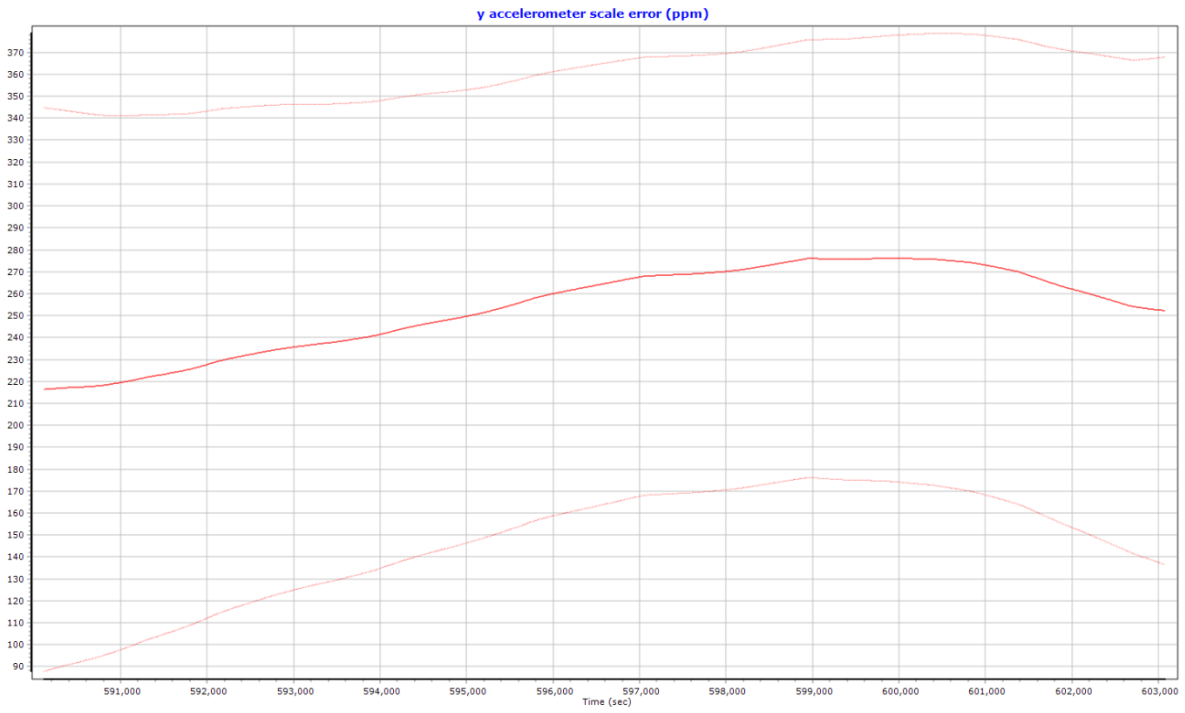
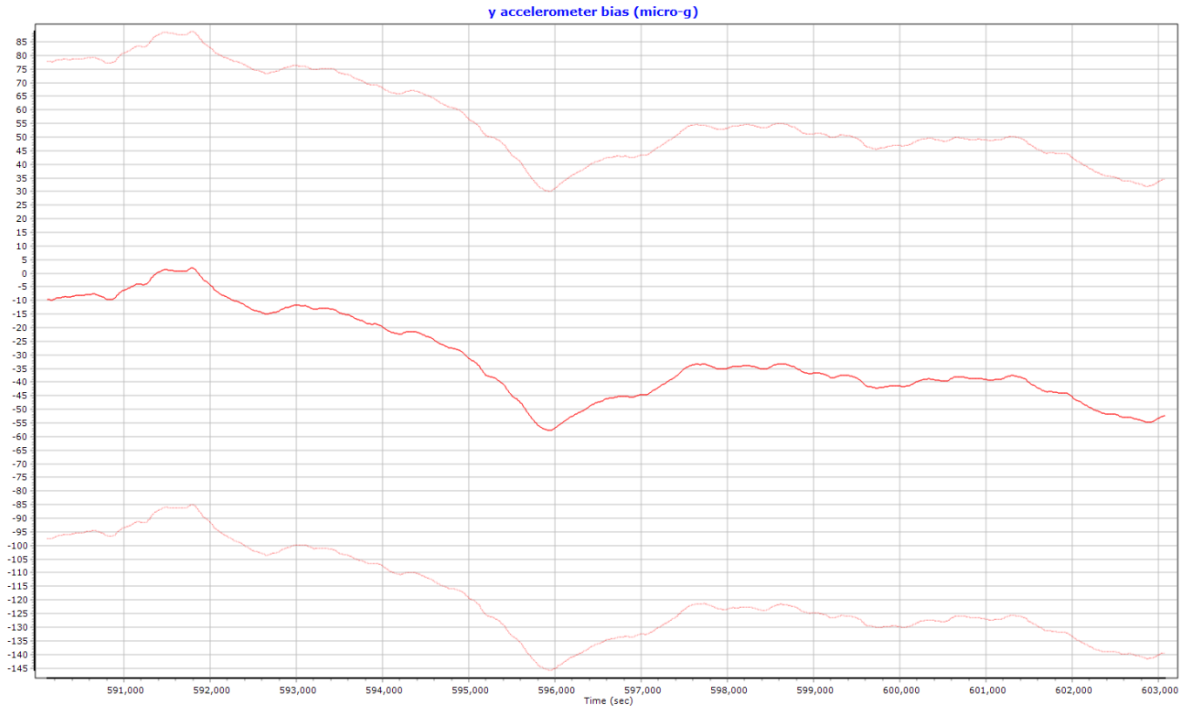
UTC Offset: 18.000

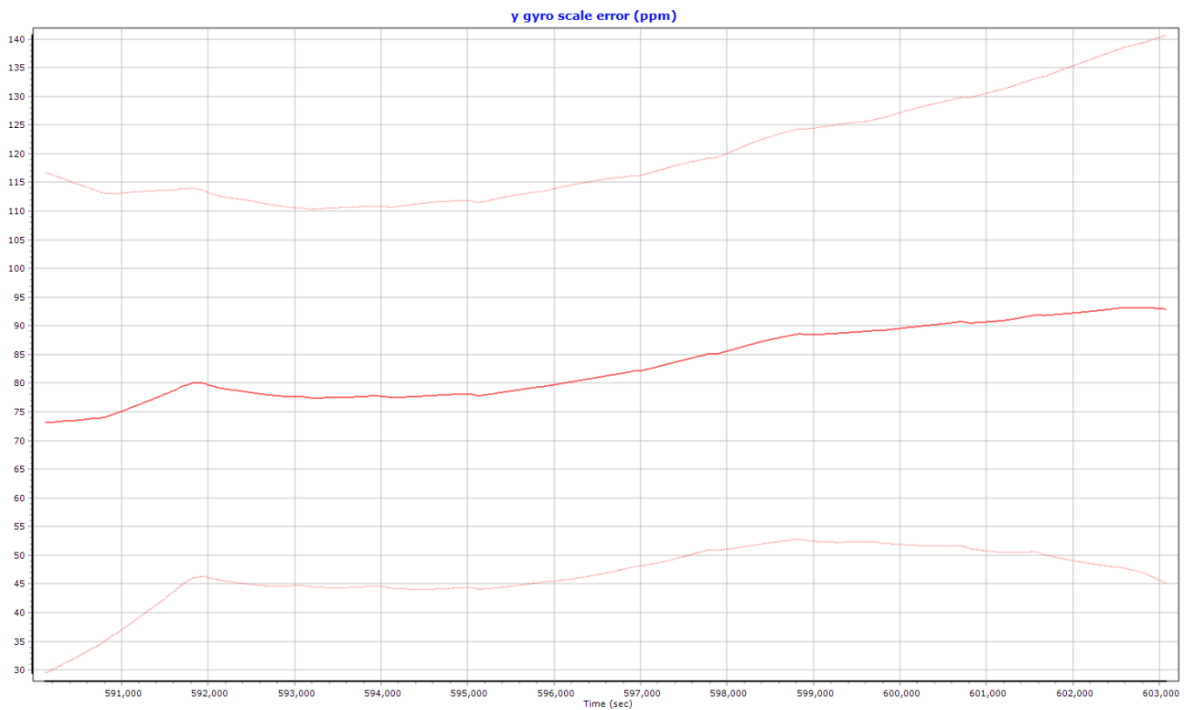
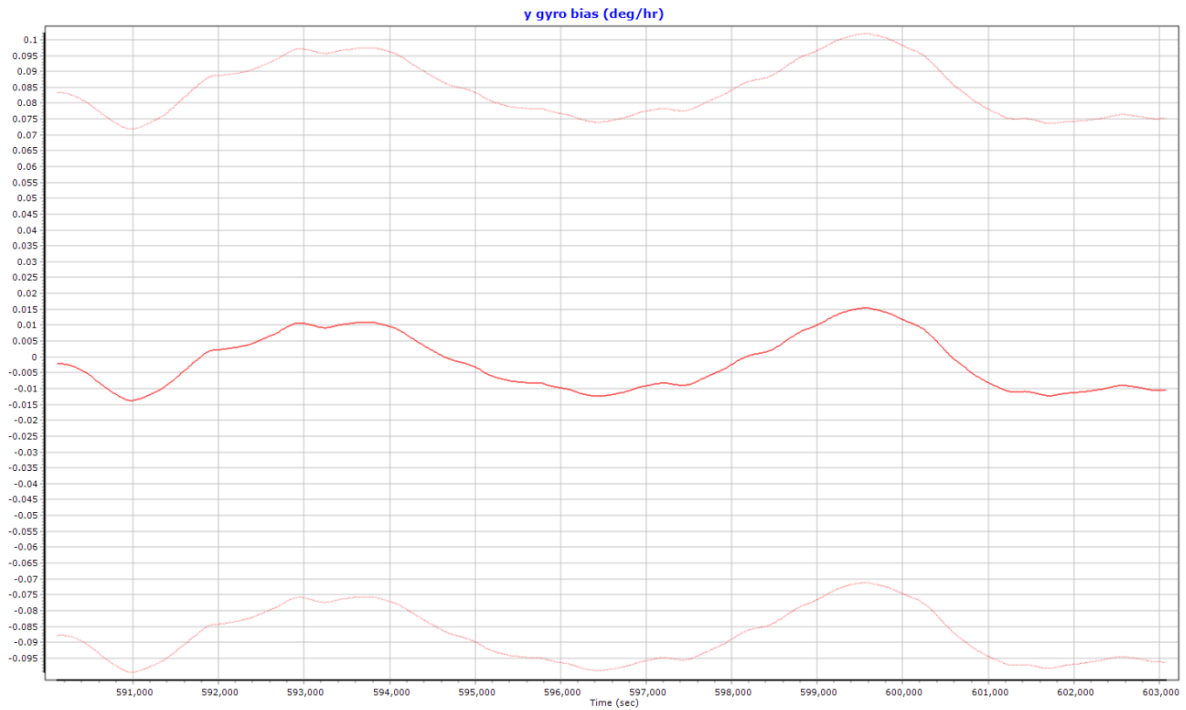
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

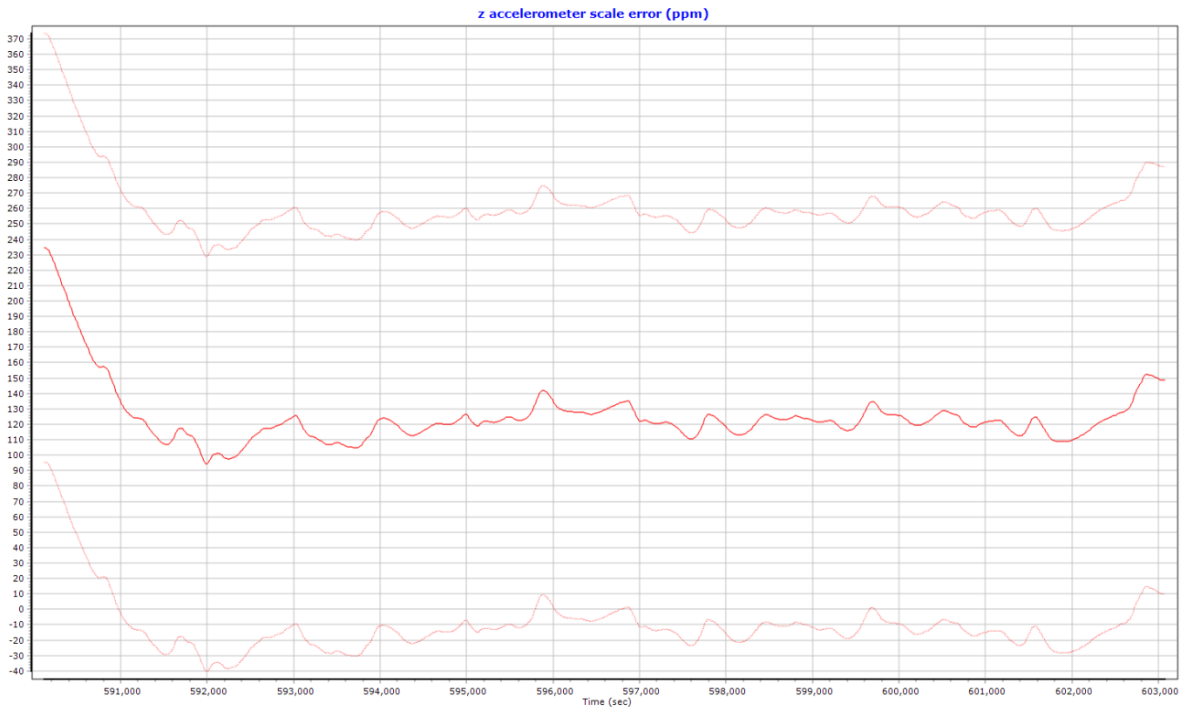
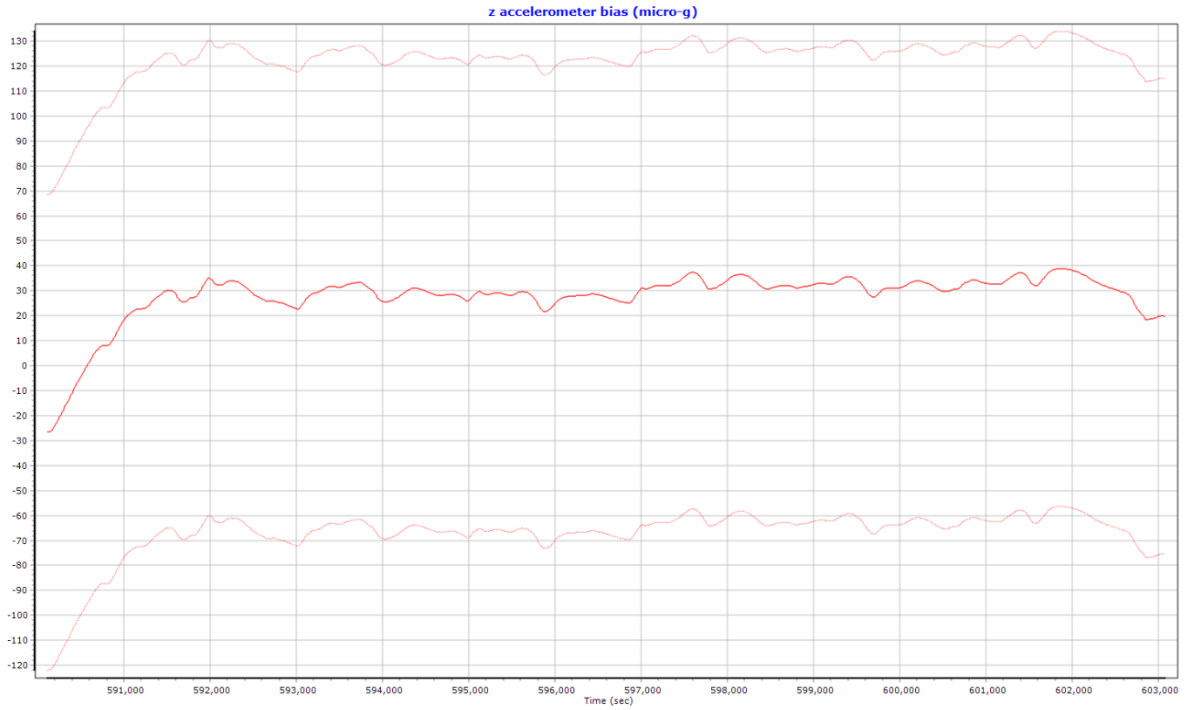
OK Cancel

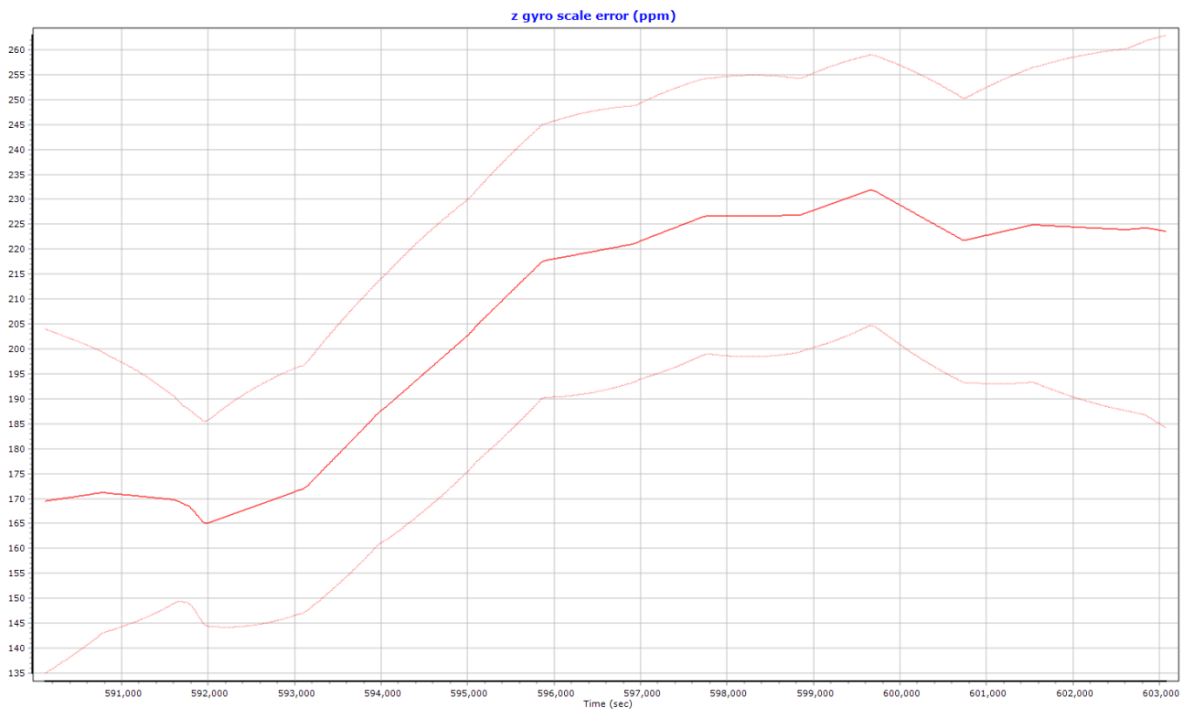
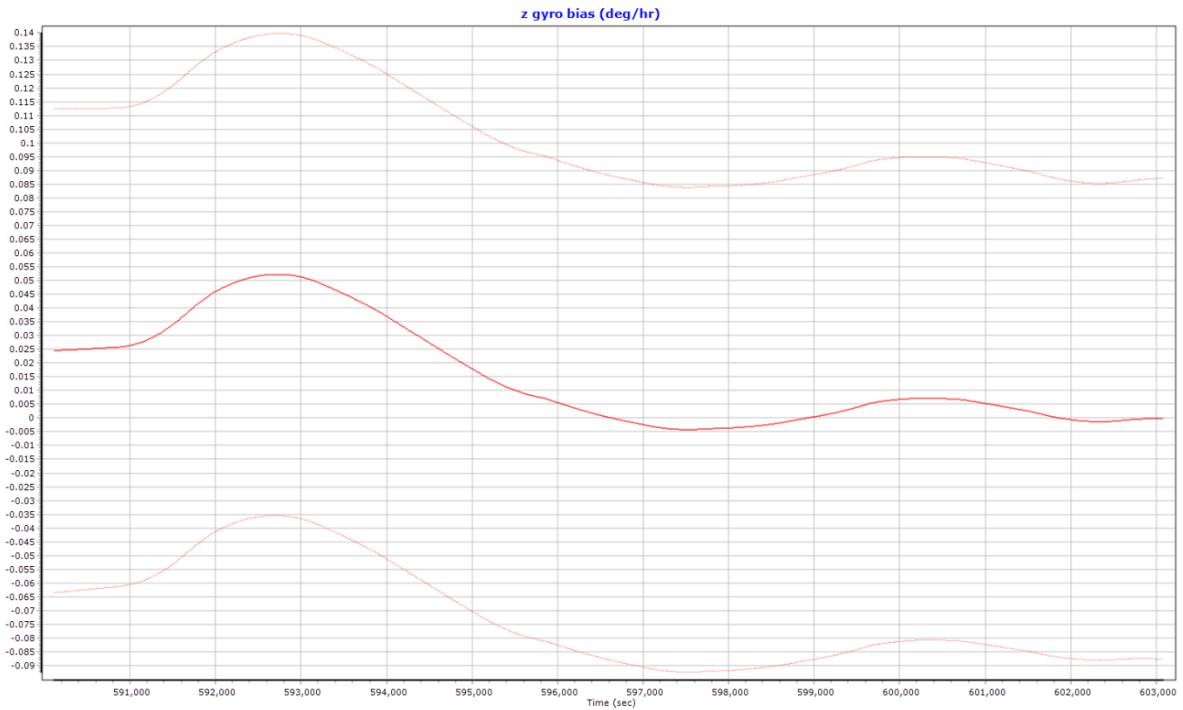




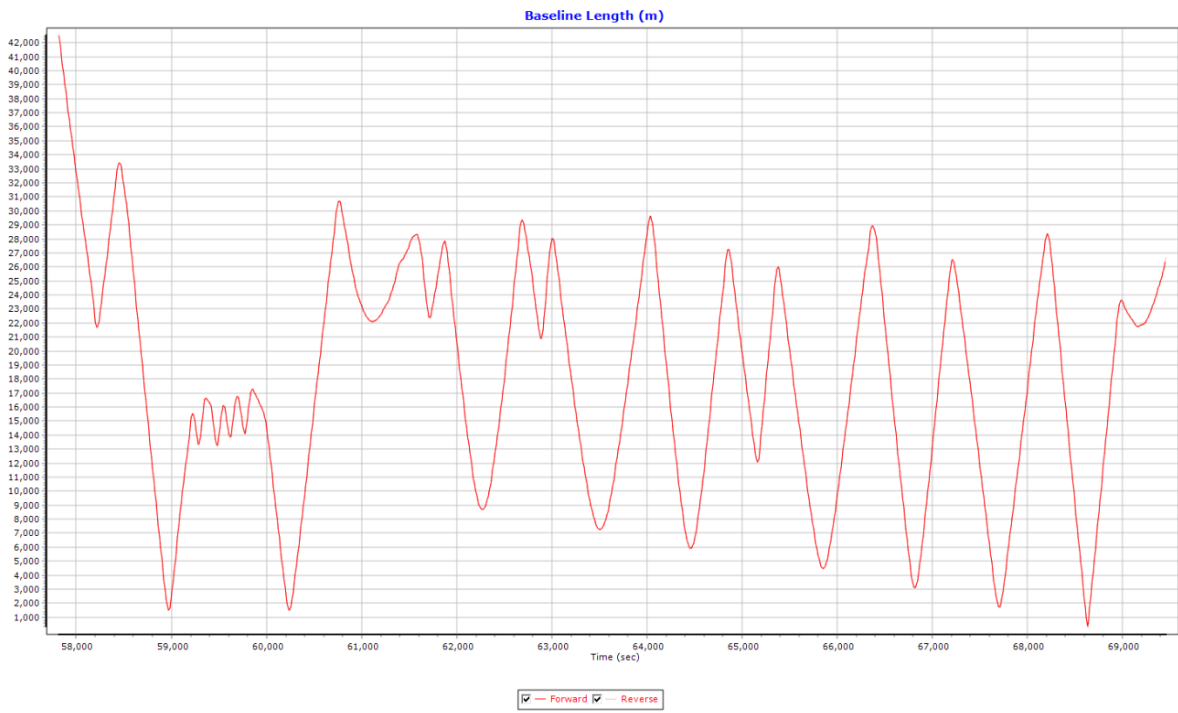
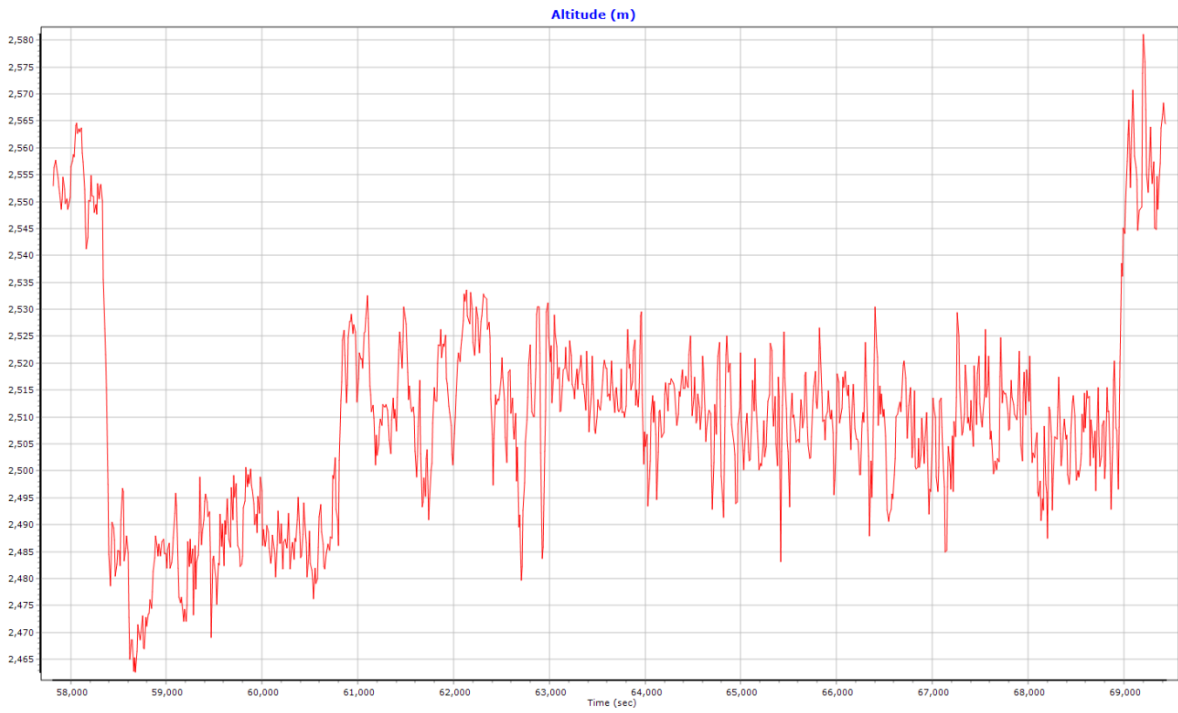


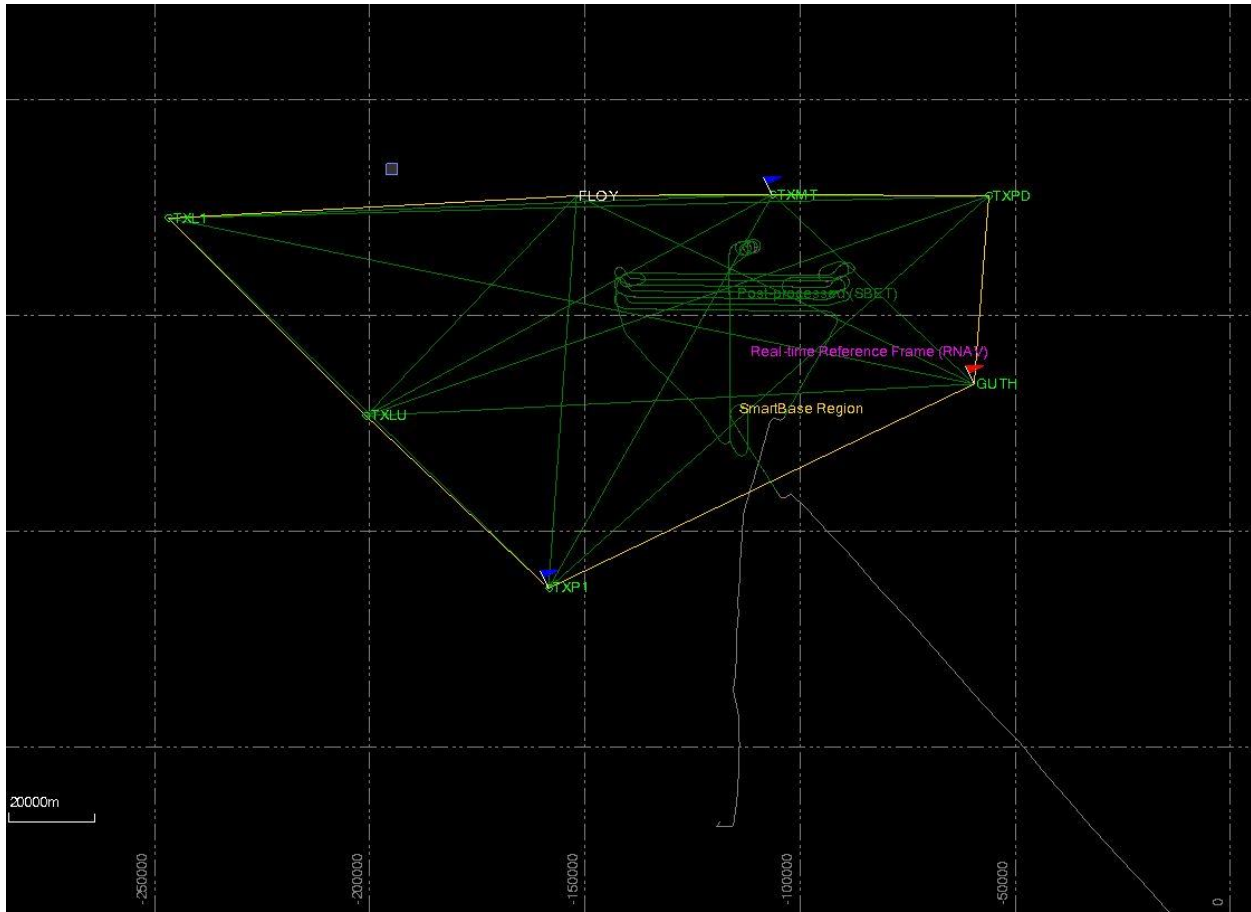






RBV18056A





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: 0.000 m

Y: 0.000 m

Z: 0.000 m

Stabilized Mount to Primary GNSS Lever Arm

X: -0.031 m

Y: 0.004 m

Z: -0.611 m

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

Stabilized Mount to IMU Mounting Angles

X: 0.000 deg

Y: 0.000 deg

Z: 0.000 deg

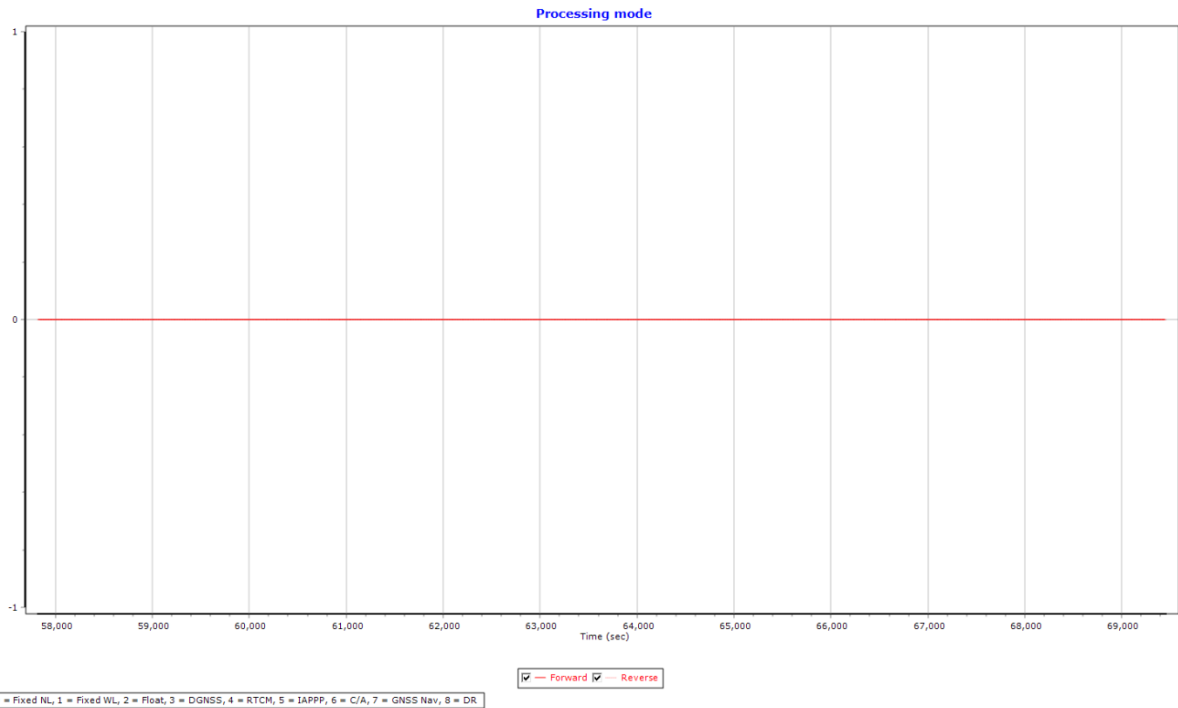
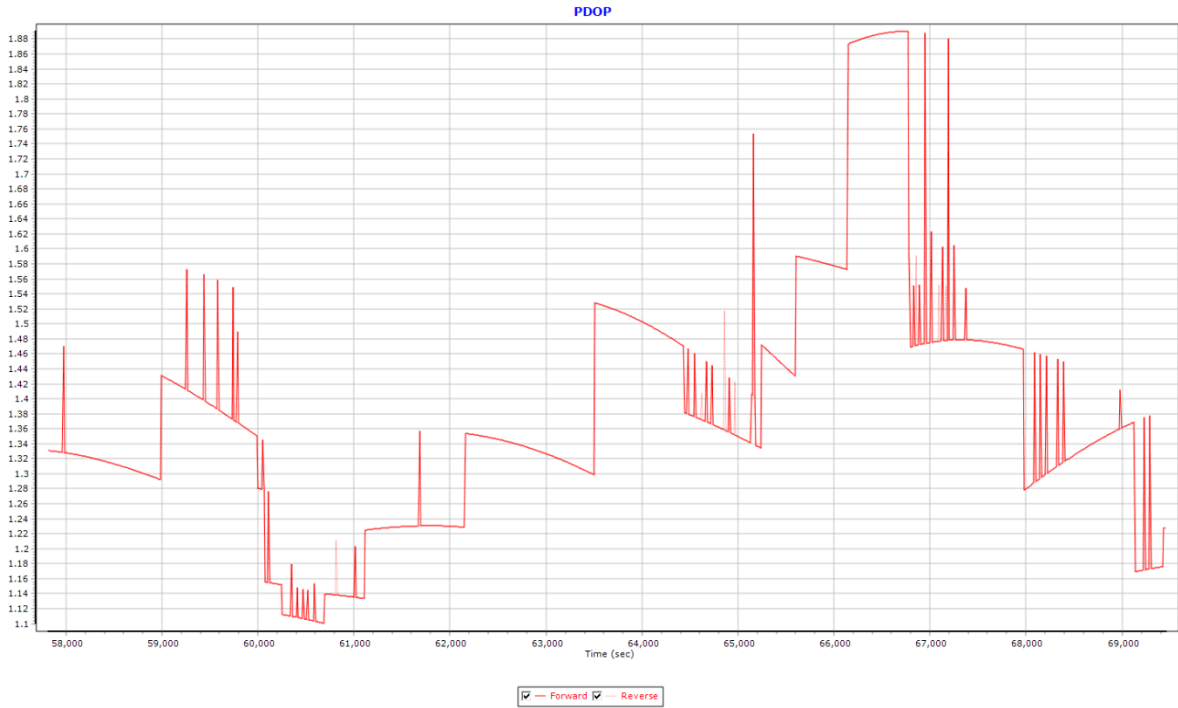
Aircraft to Stabilized Mount Mounting Angles

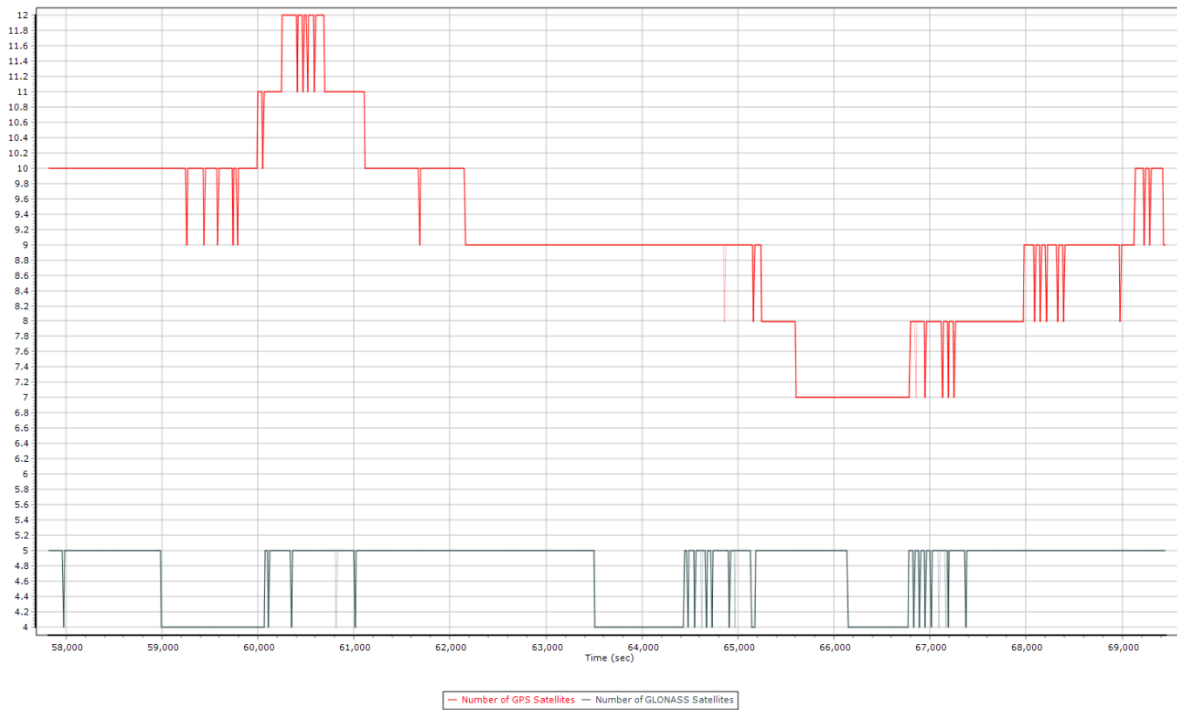
X: 0.000 deg

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.







Project Settings

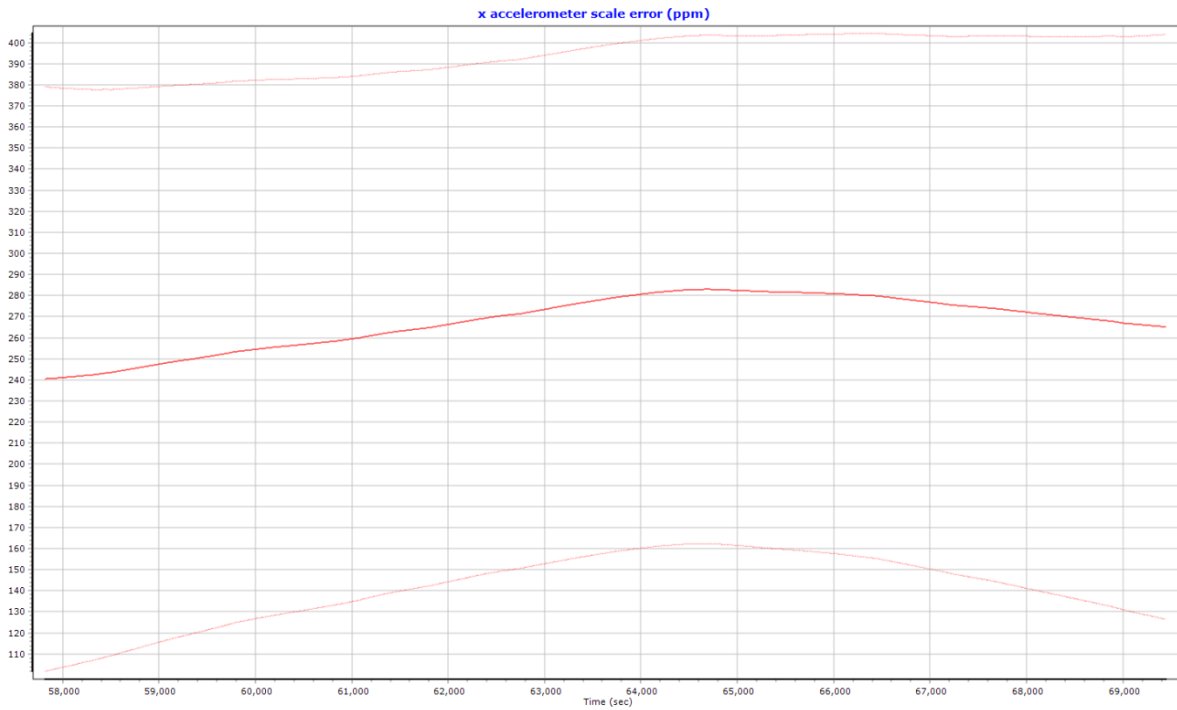
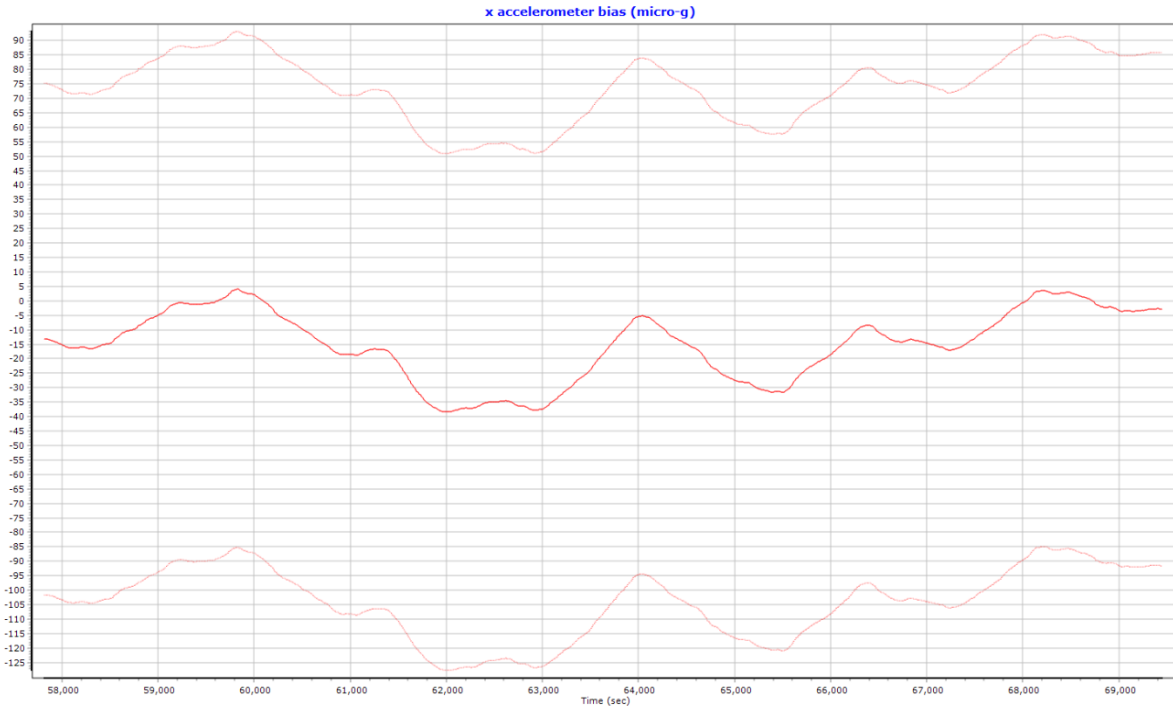
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

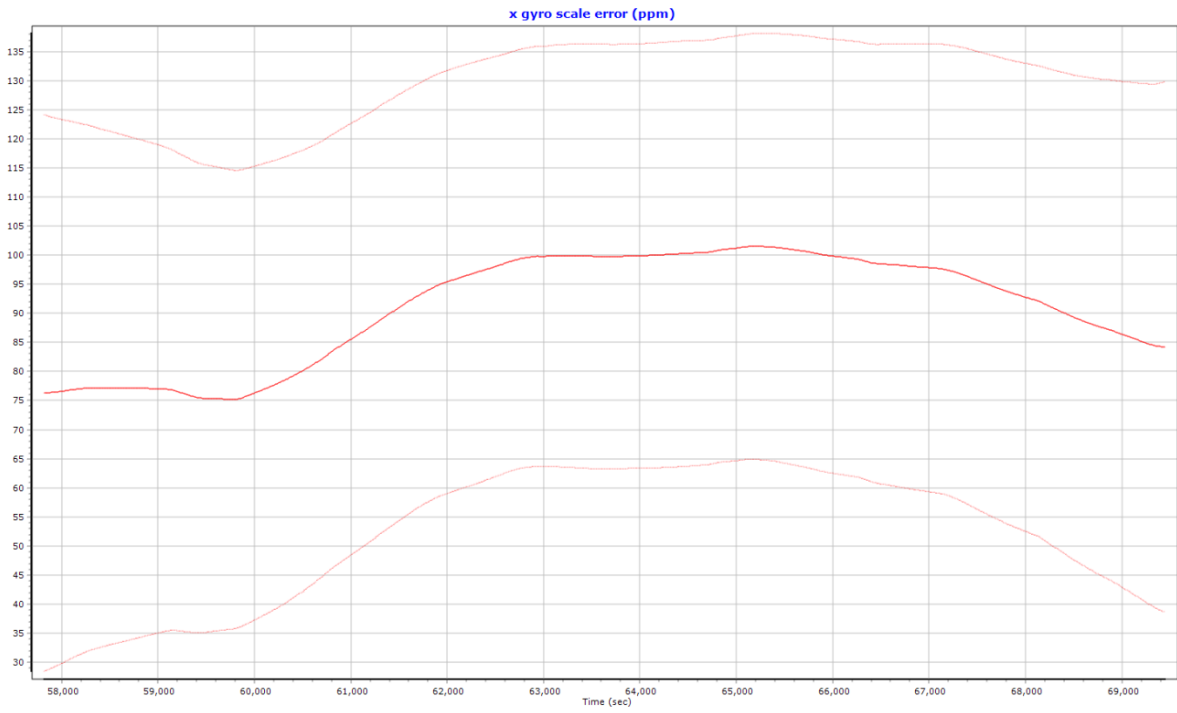
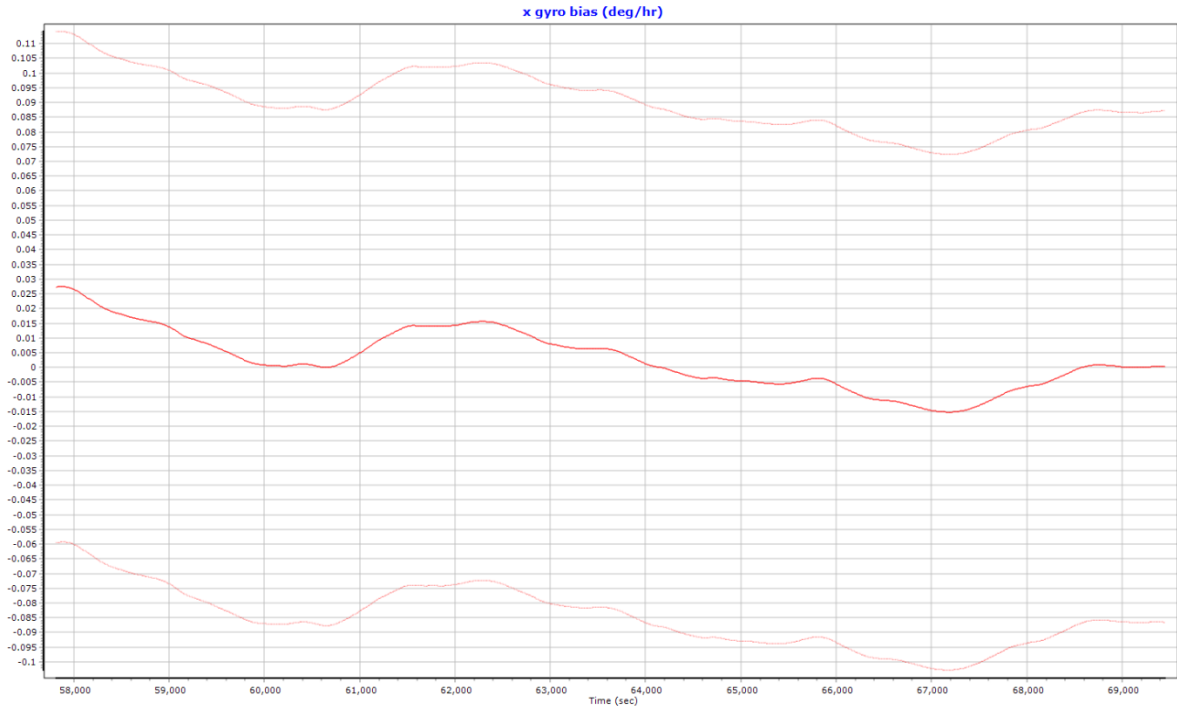
Timing

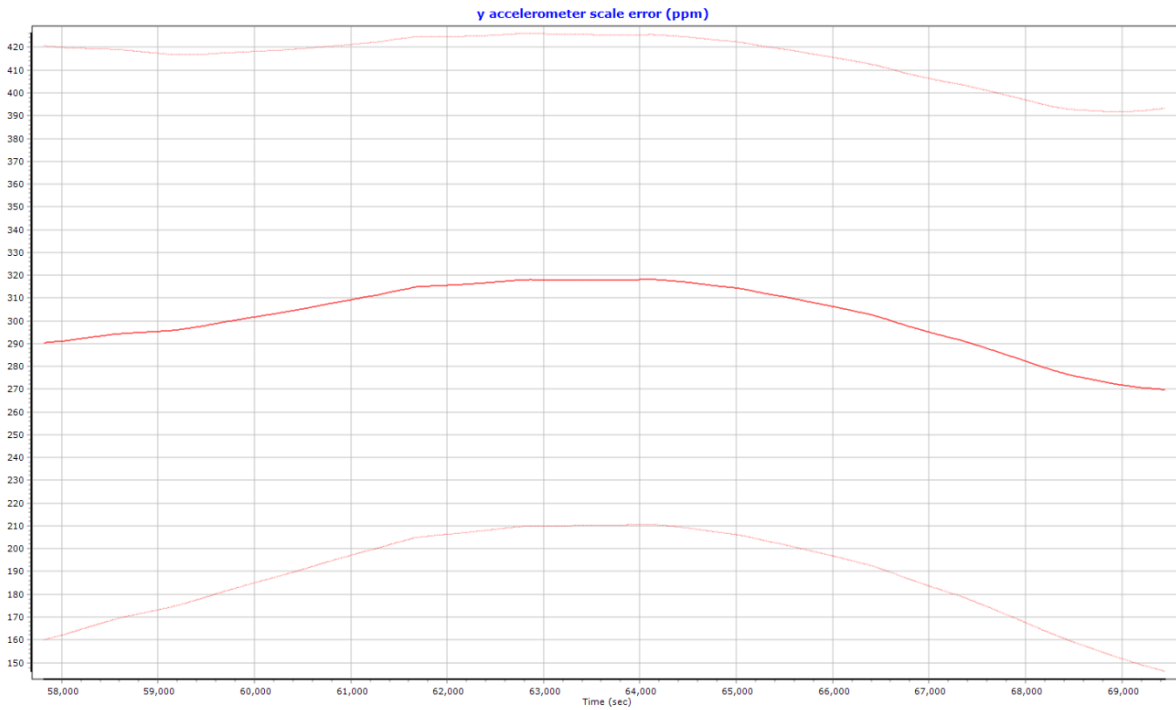
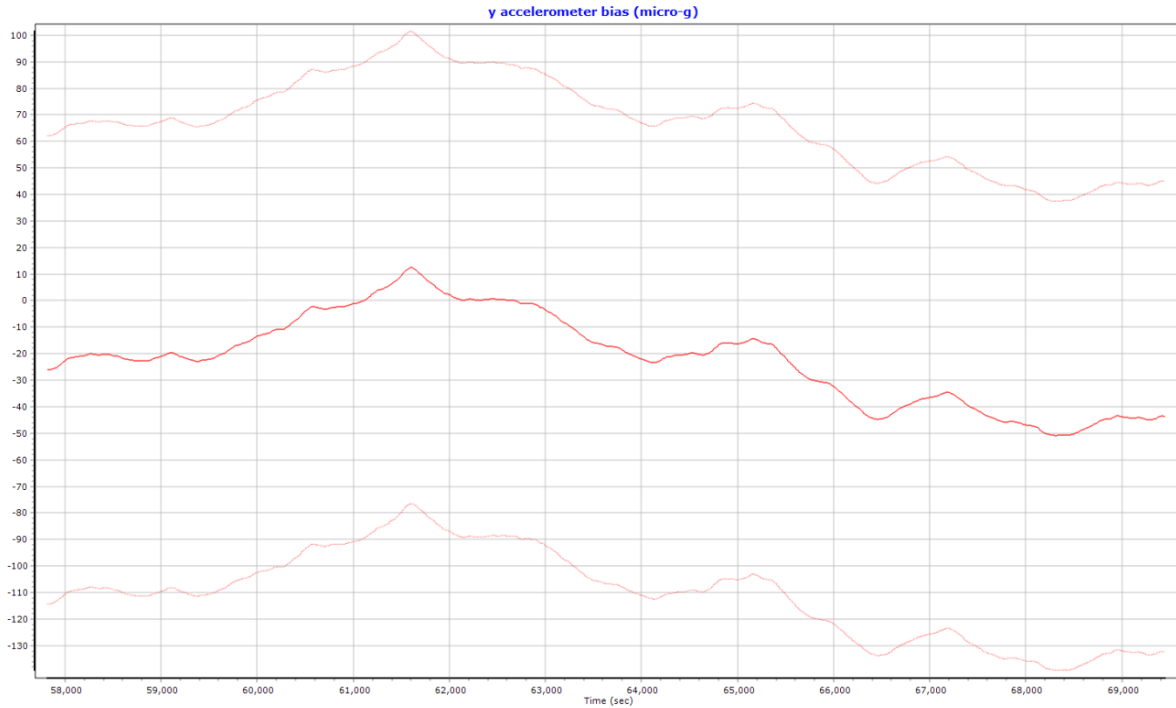
Start: 57816.132
 End: 69458.828
 Entire time interval
 Seconds of start week
 UTC Offset: 18.000

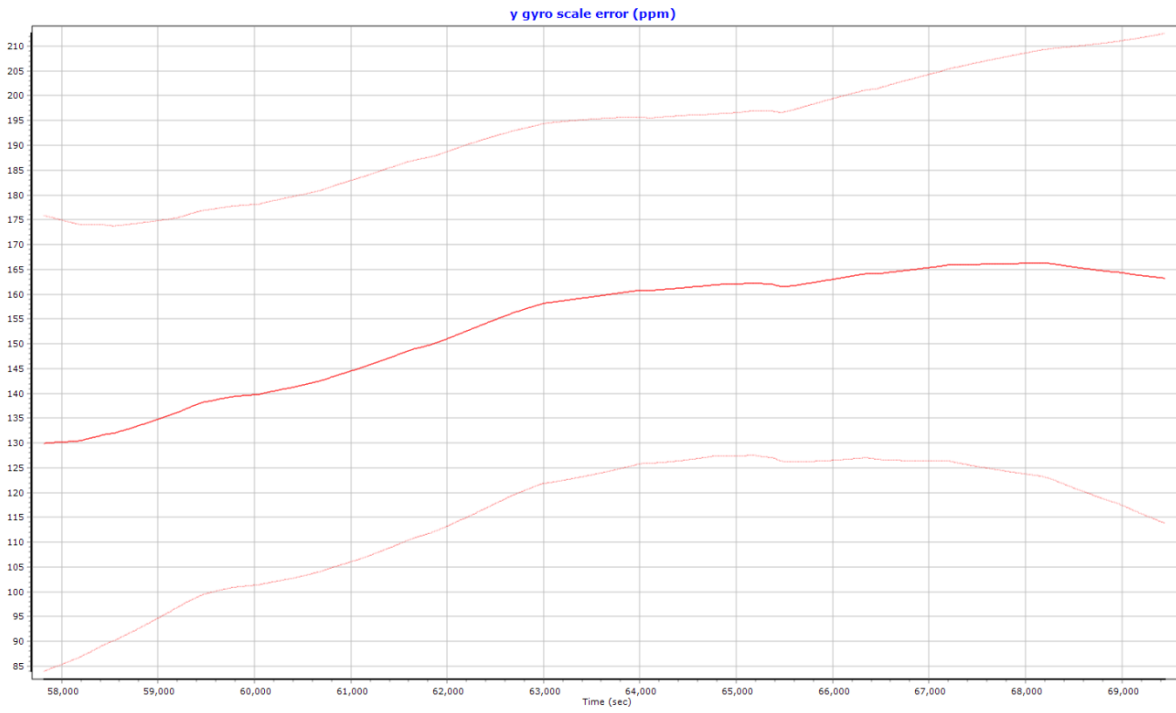
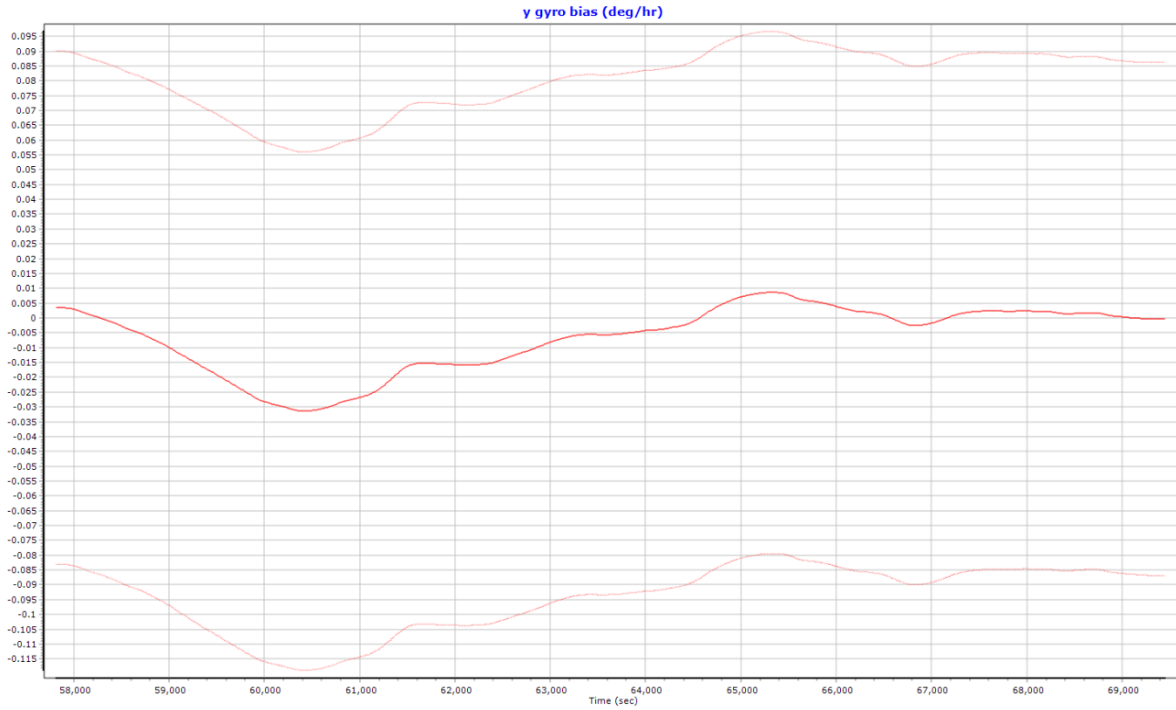
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

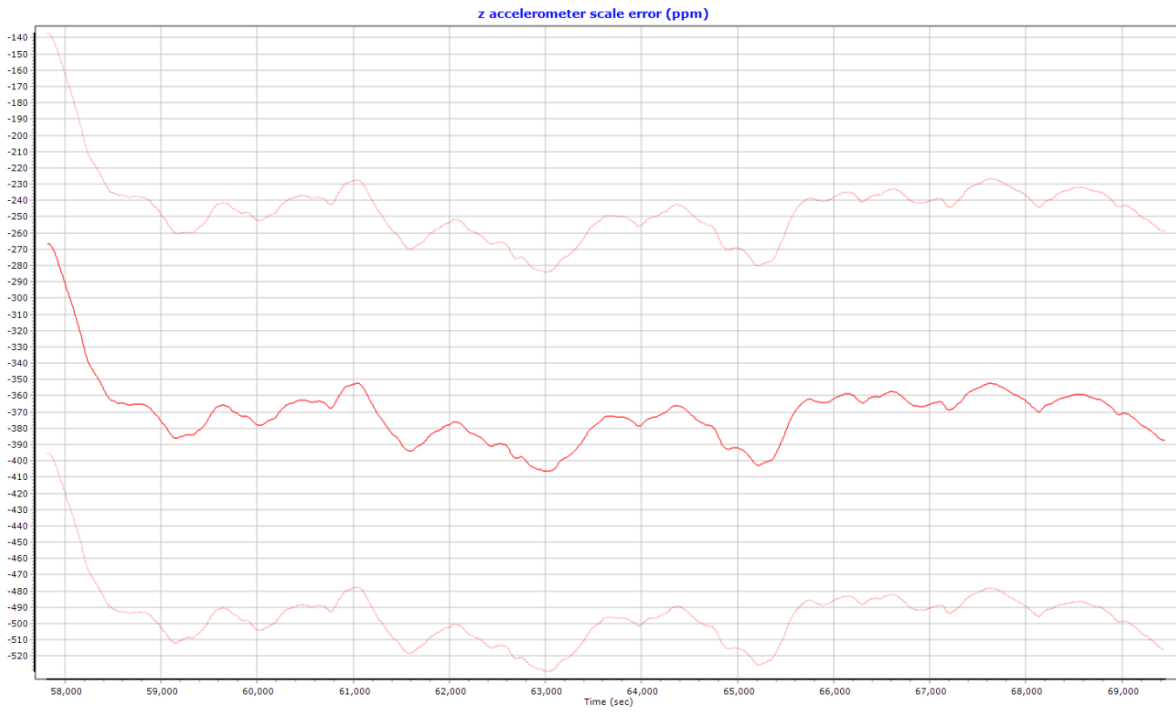
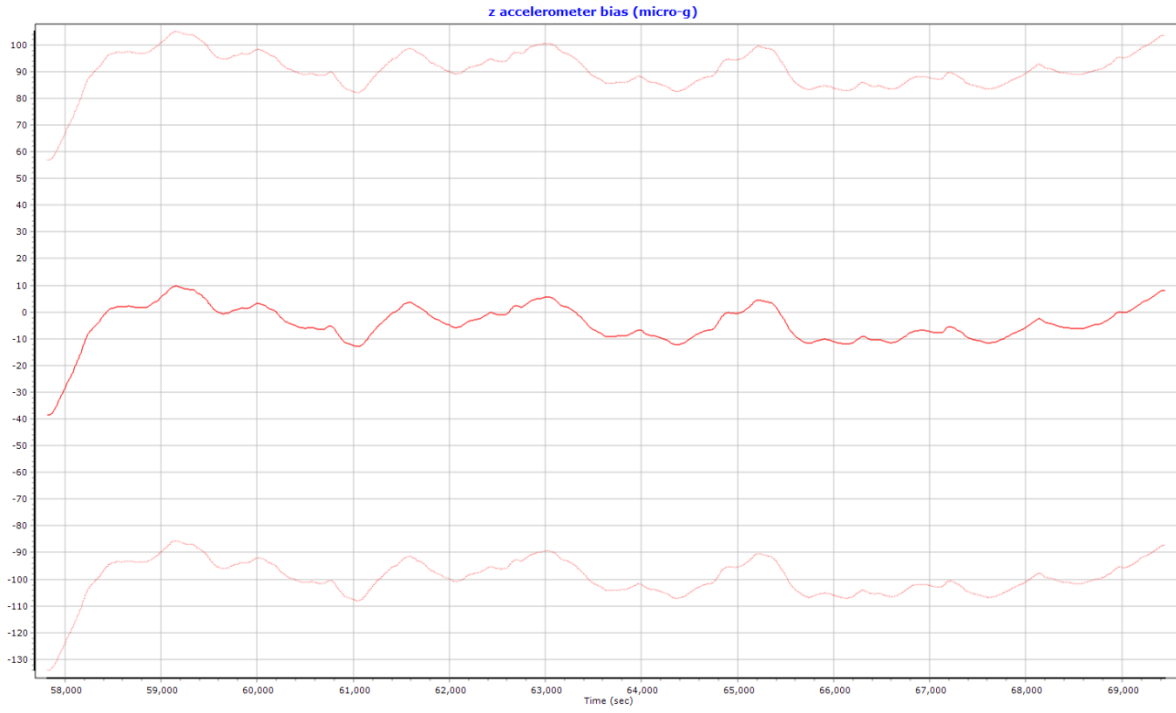
OK Cancel

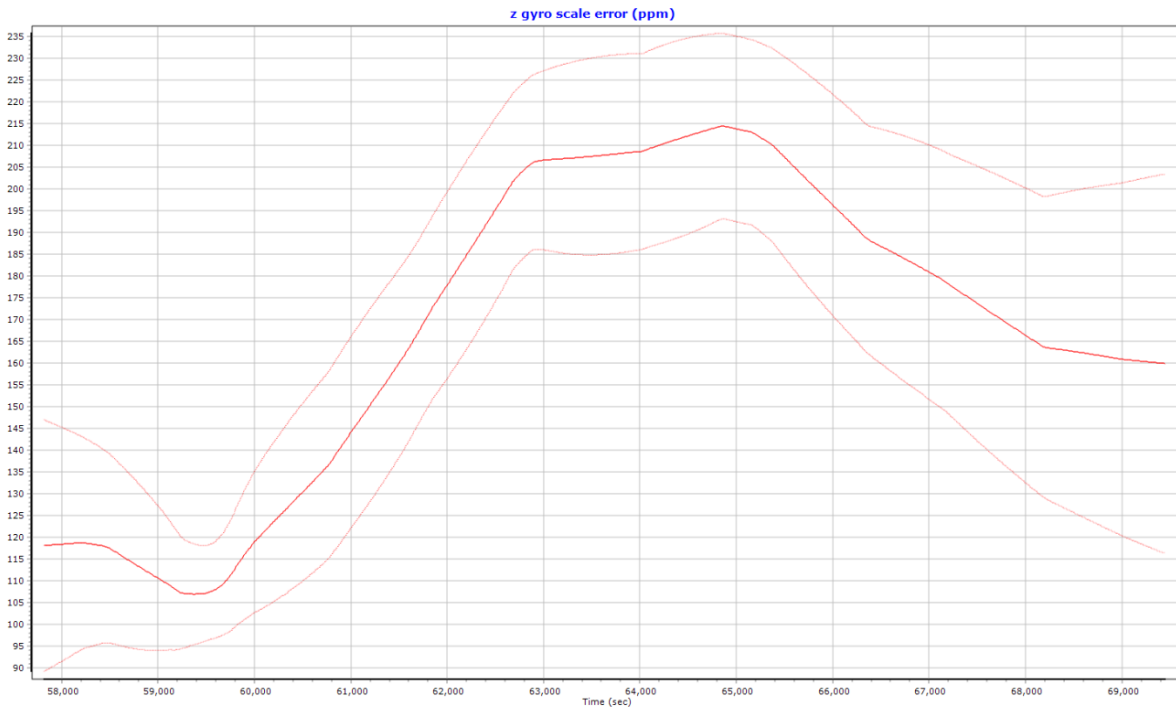
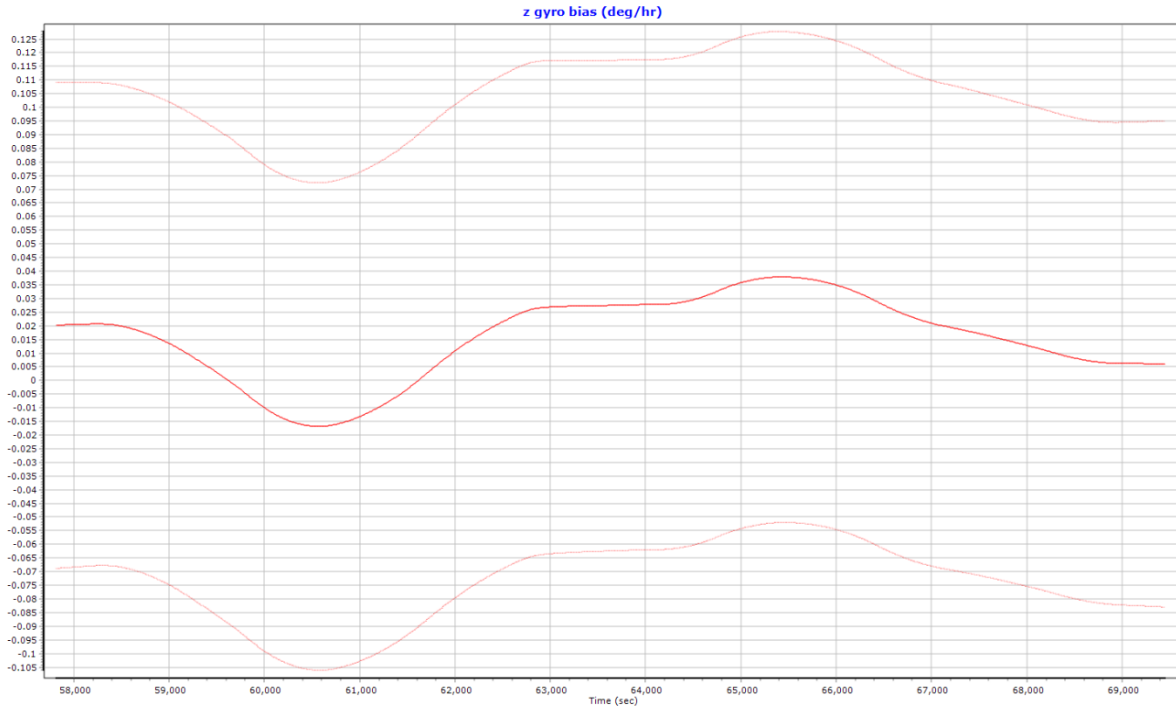




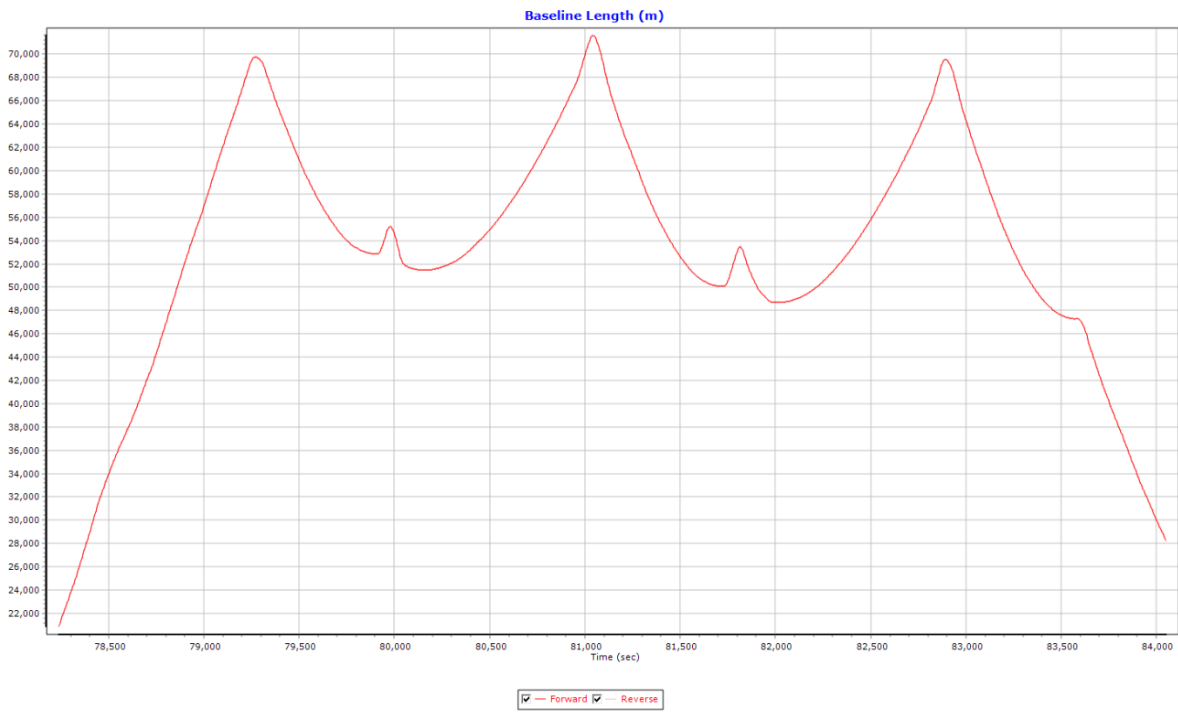
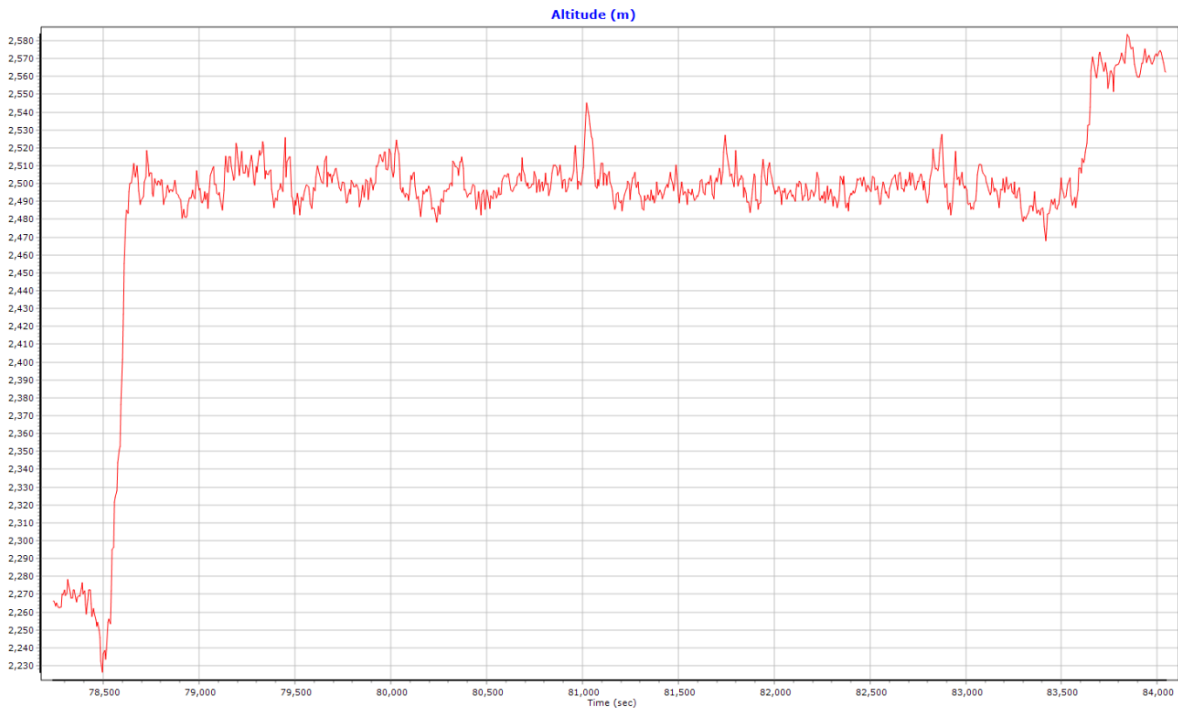


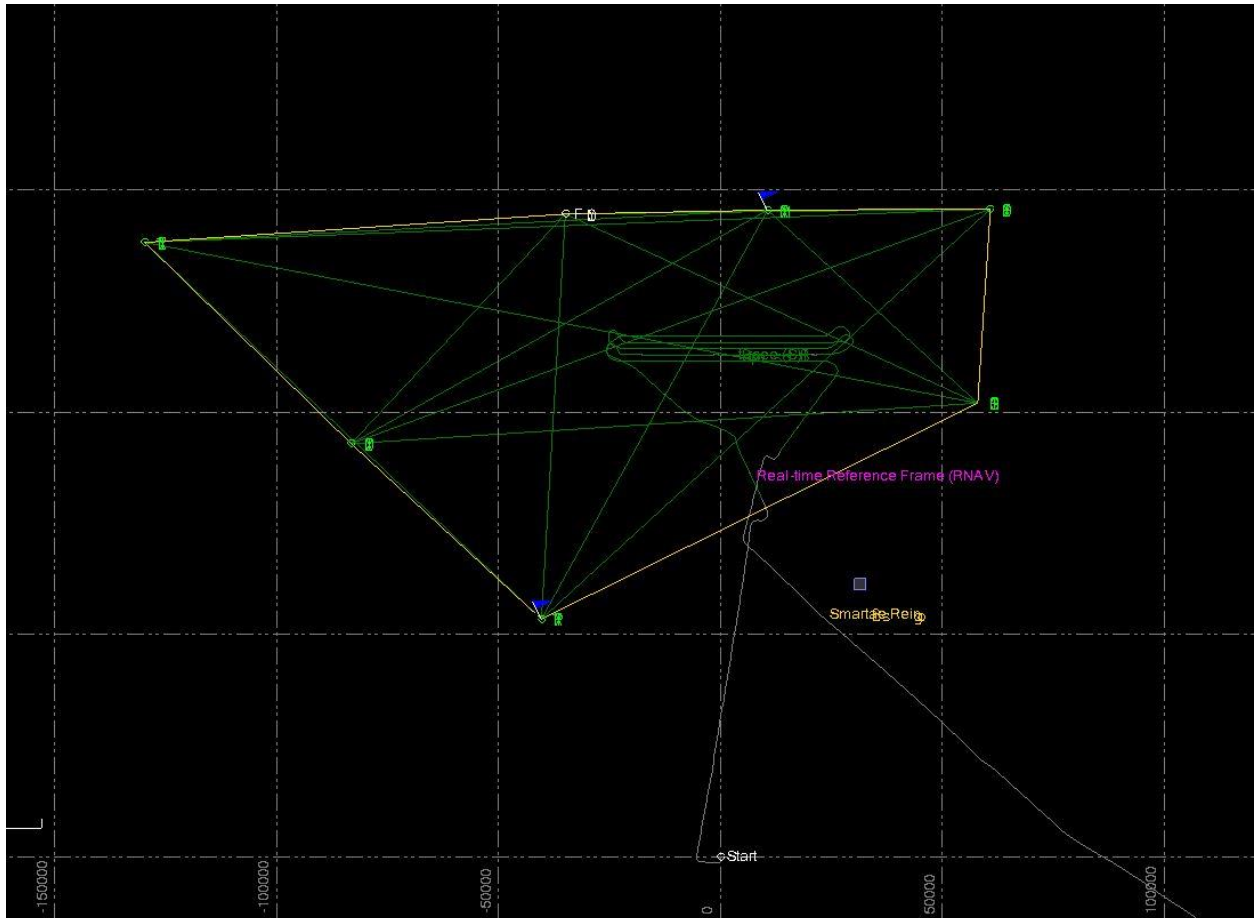






RBV18056B





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:

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

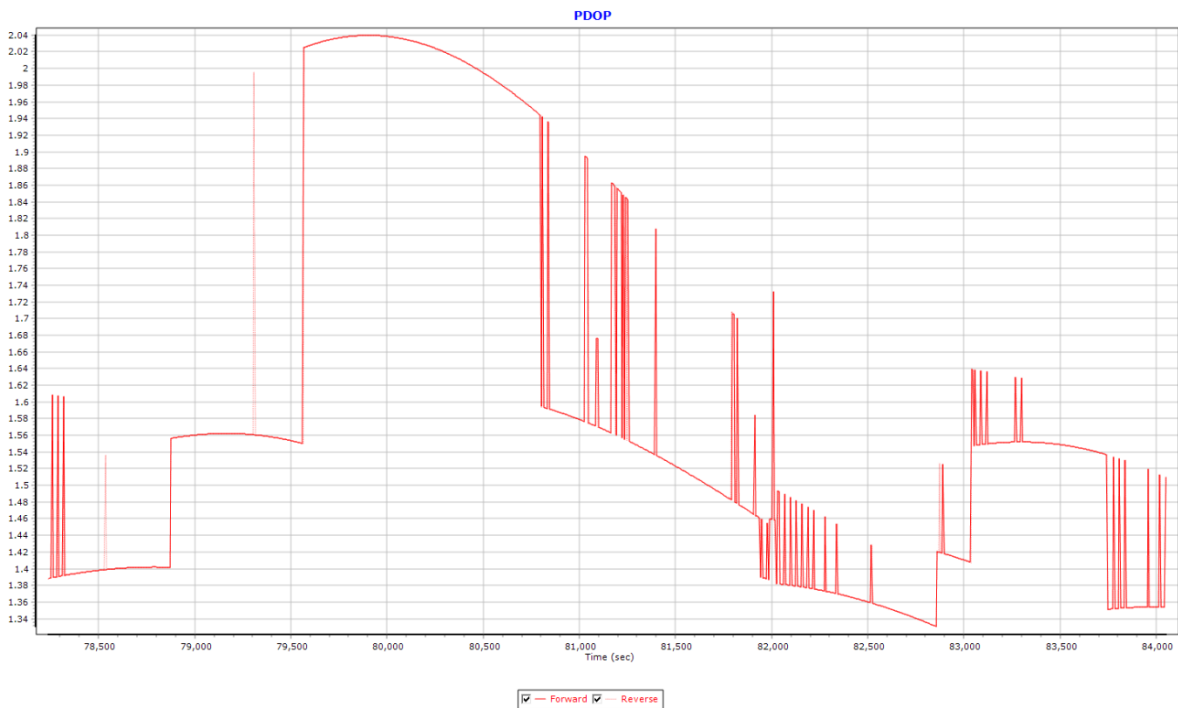
Aircraft to Stabilized Mount Mounting Angles

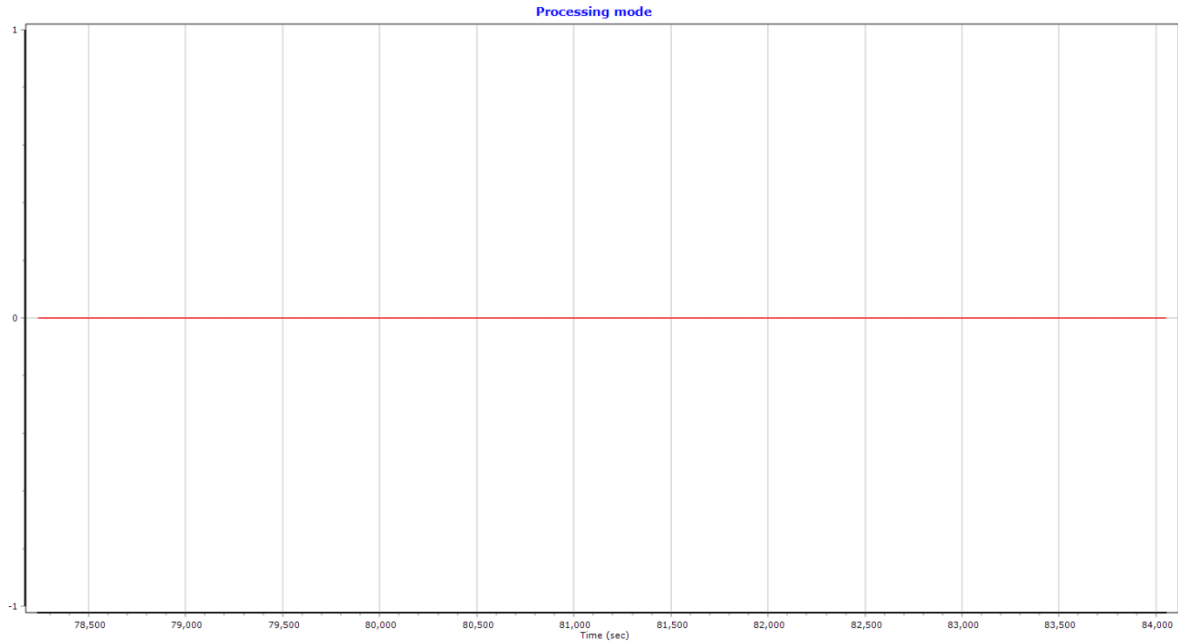
X:

Y:

Z:

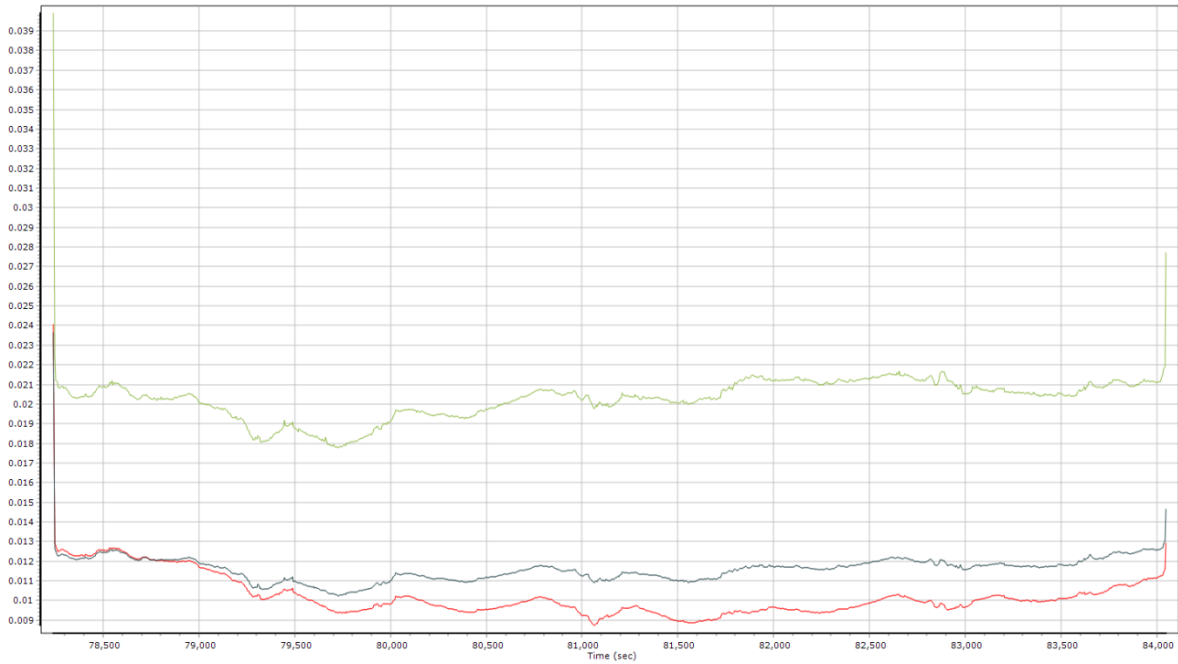
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.



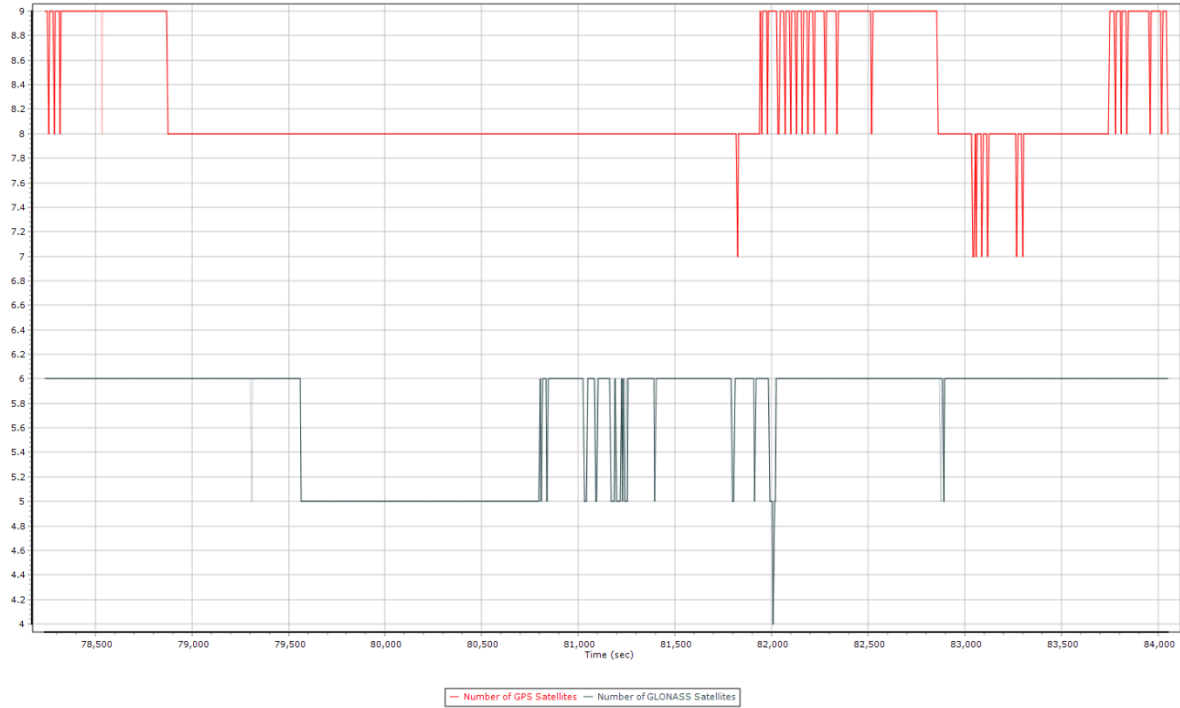


Forward Reverse

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



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



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

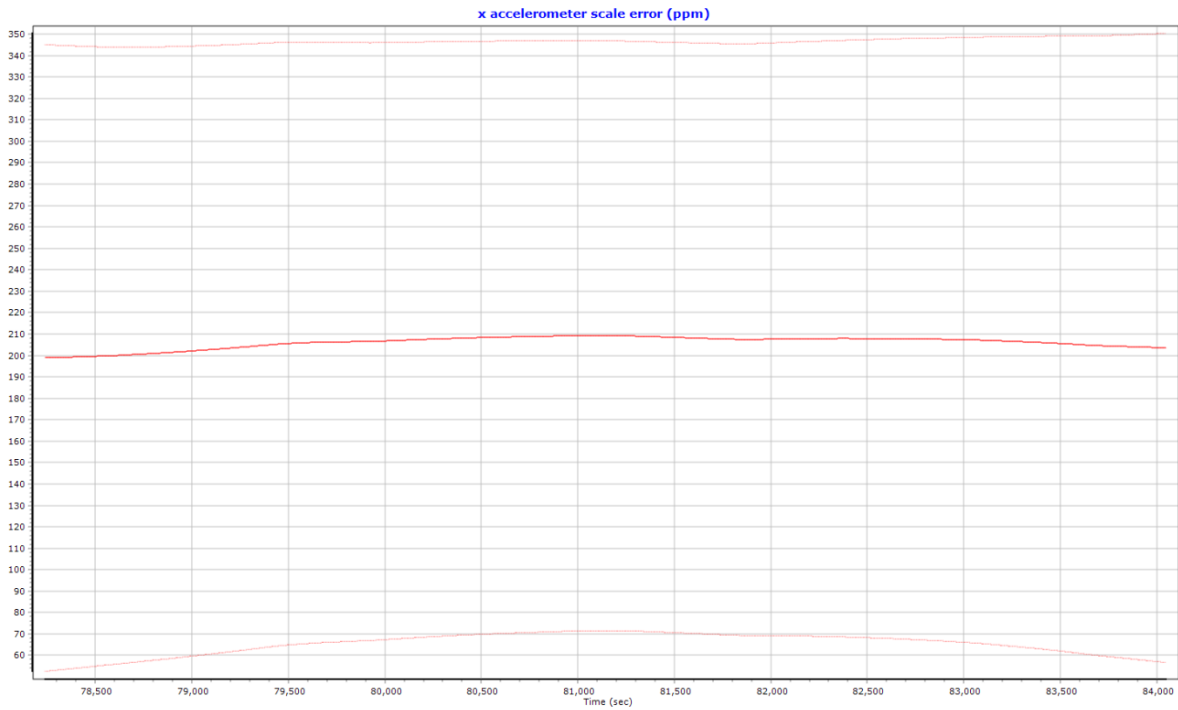
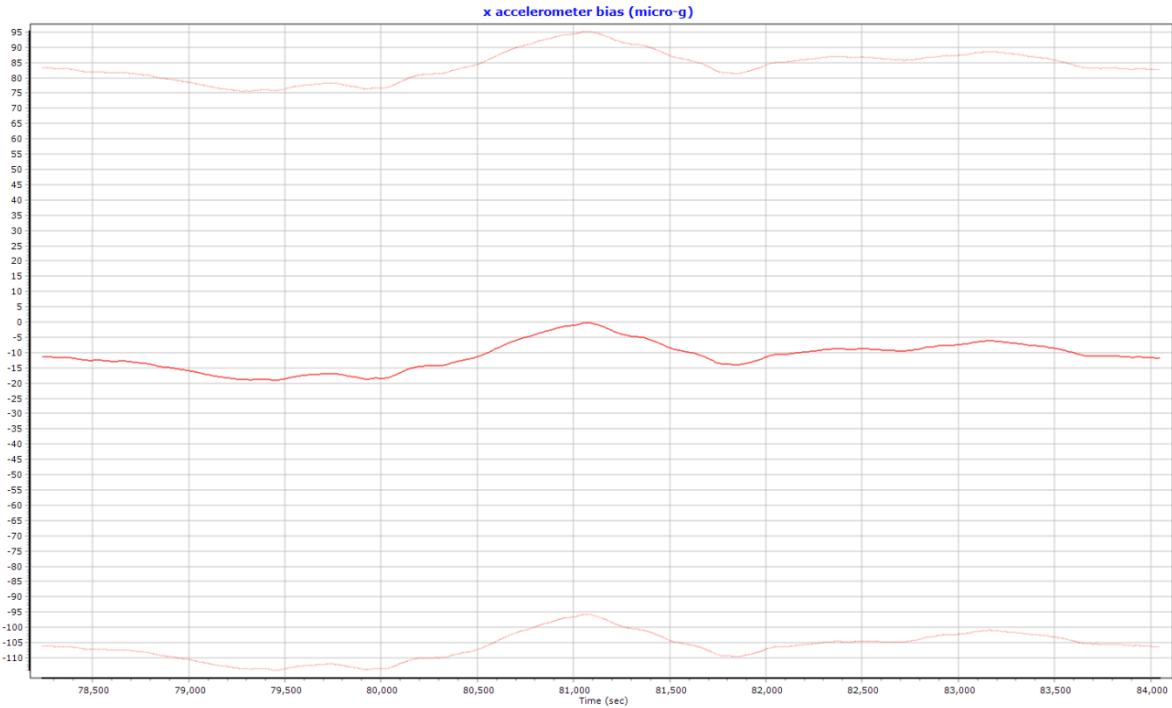
Start: 78236.380
End: 84052.739

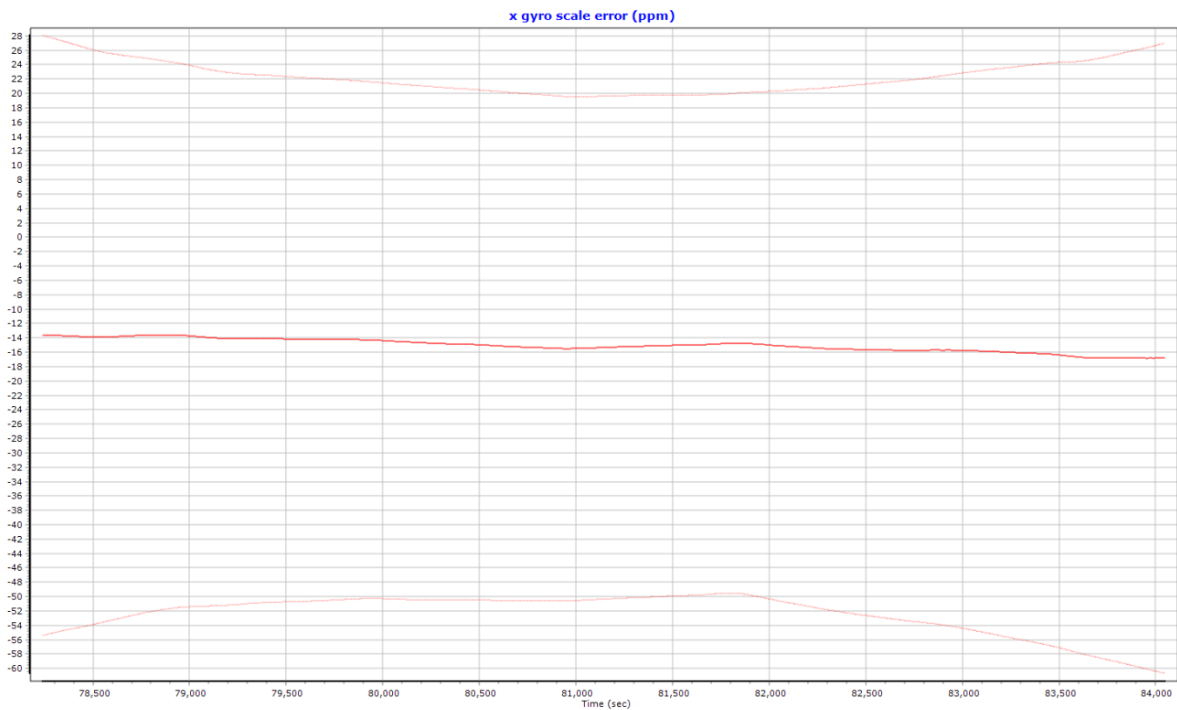
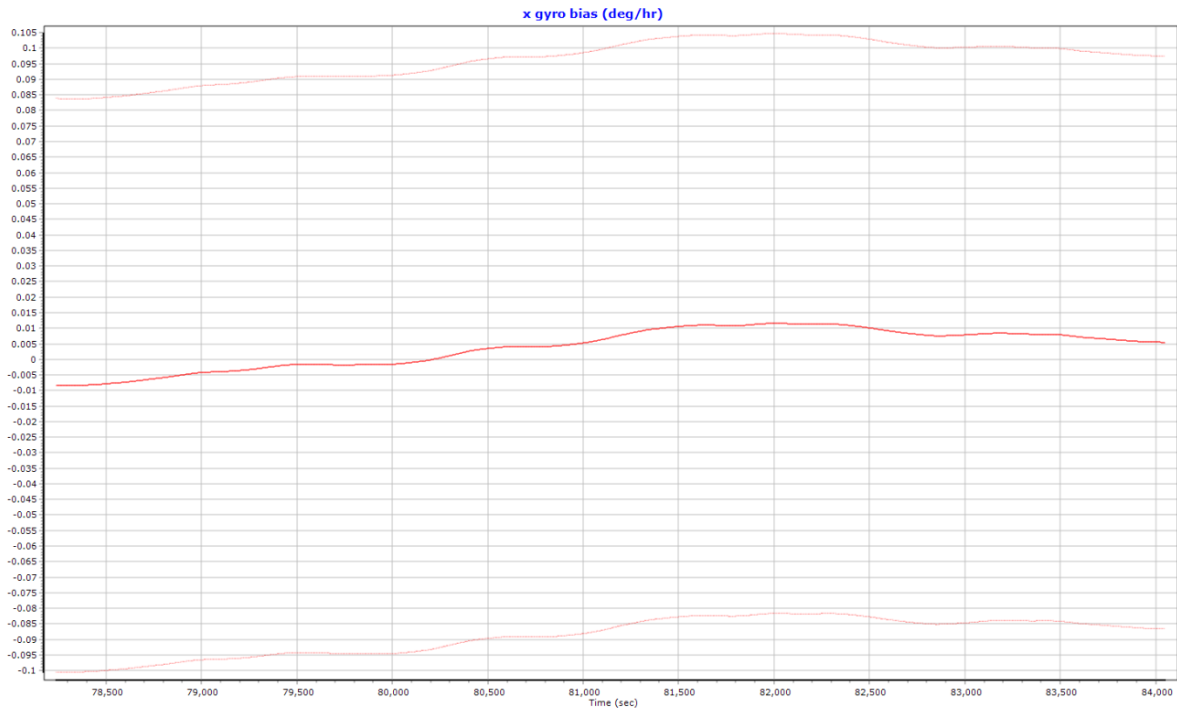
Entire time interval
 Seconds of start week

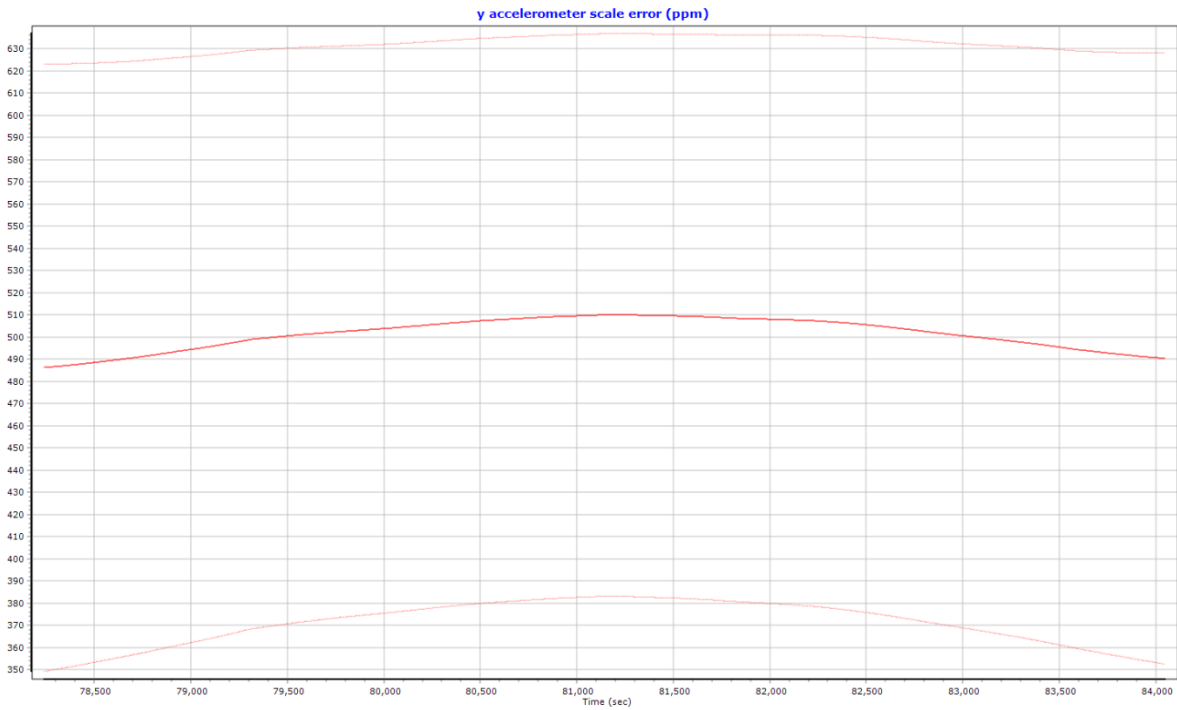
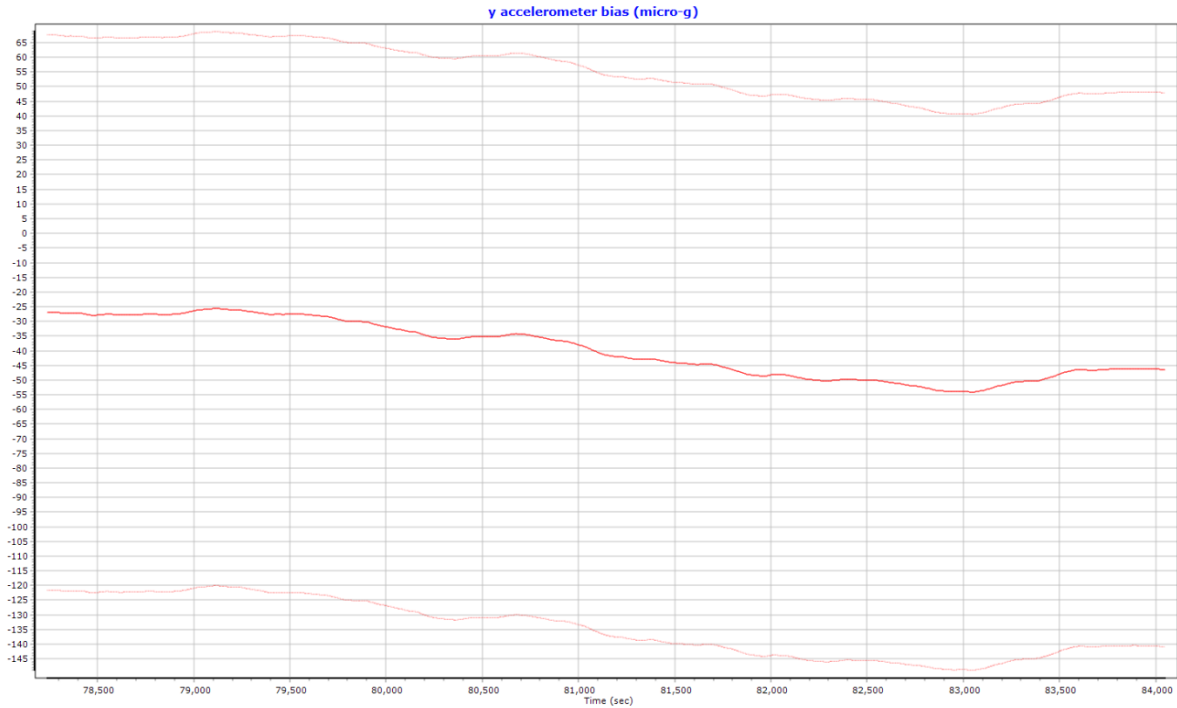
UTC Offset: 18.000

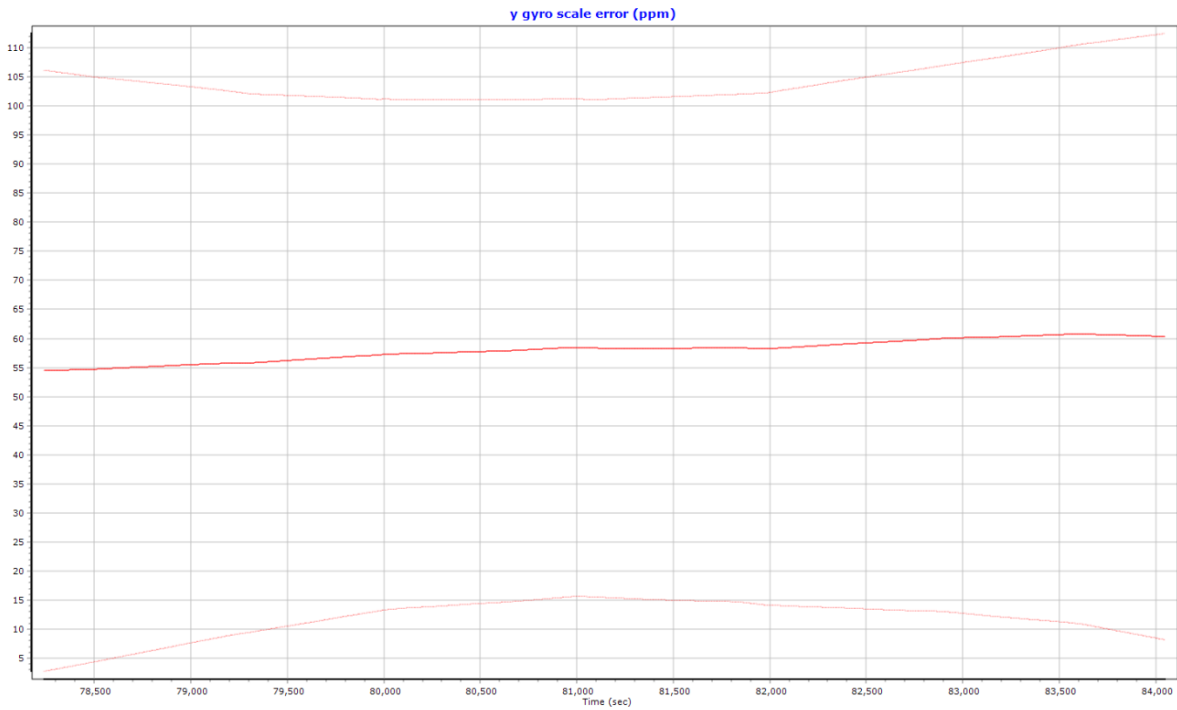
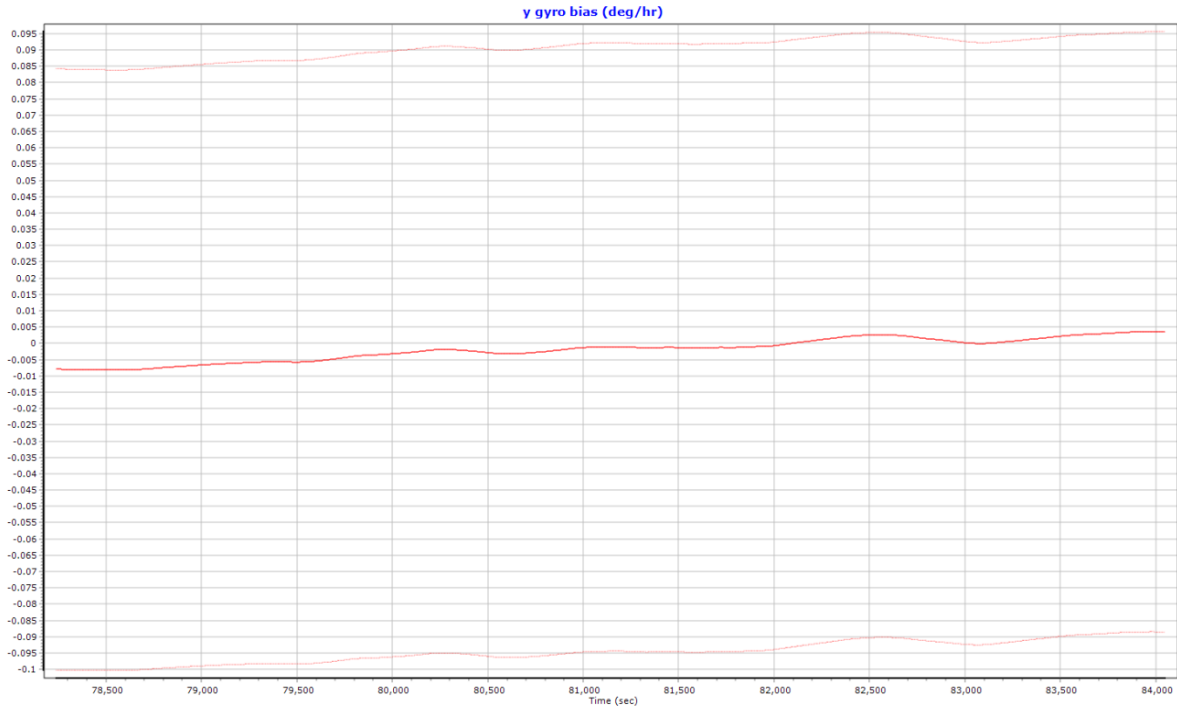
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

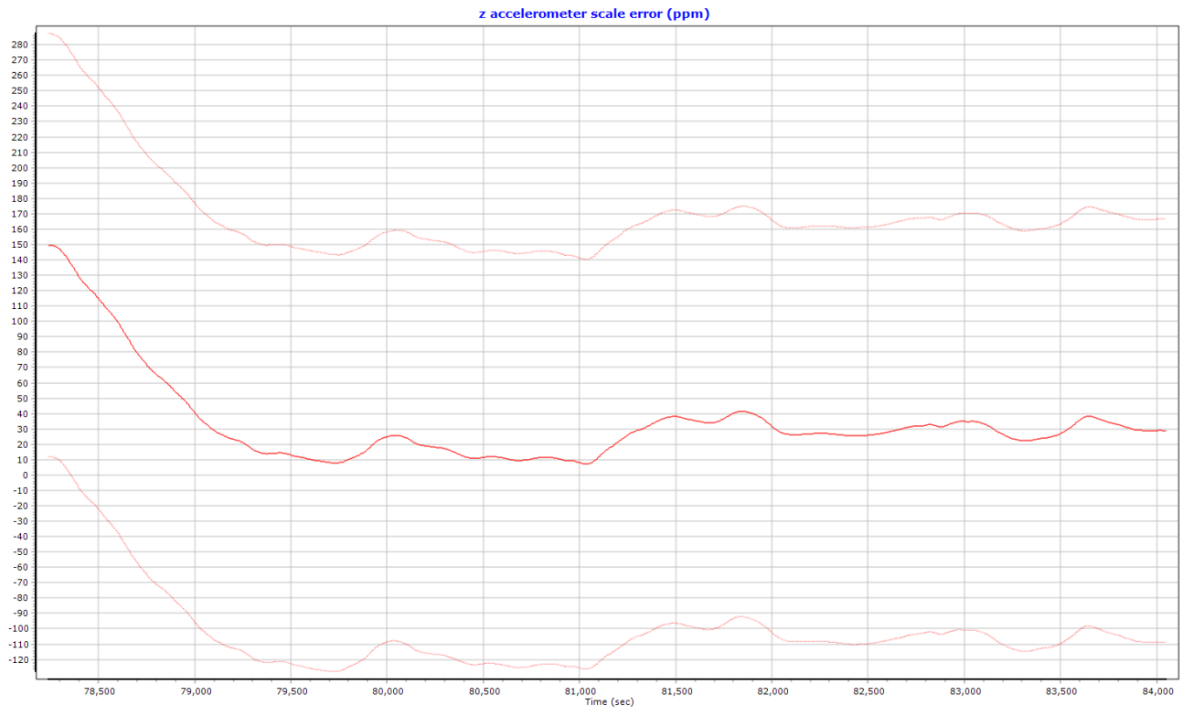
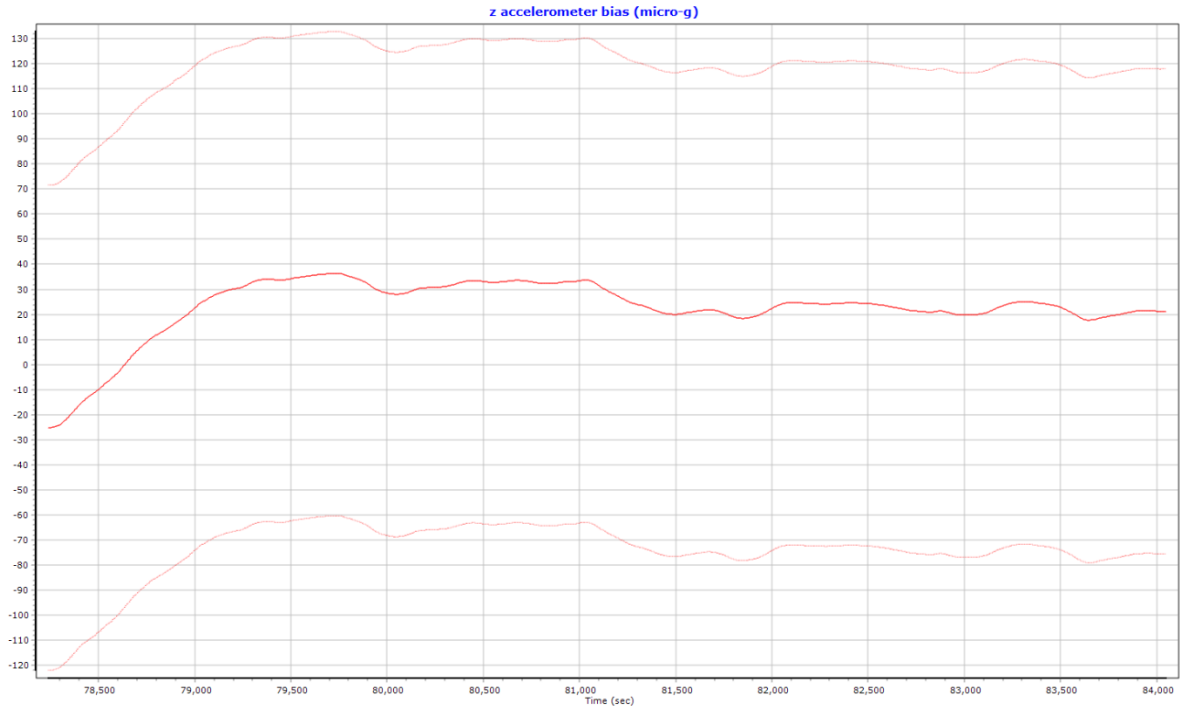
OK Cancel

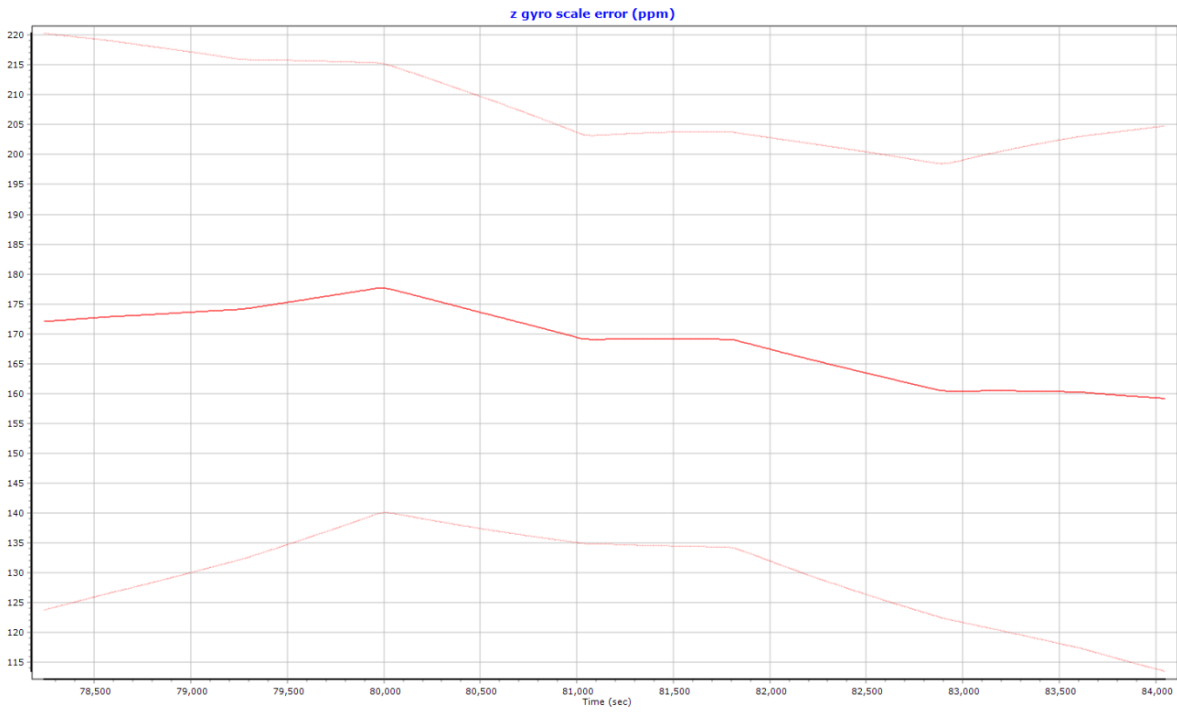
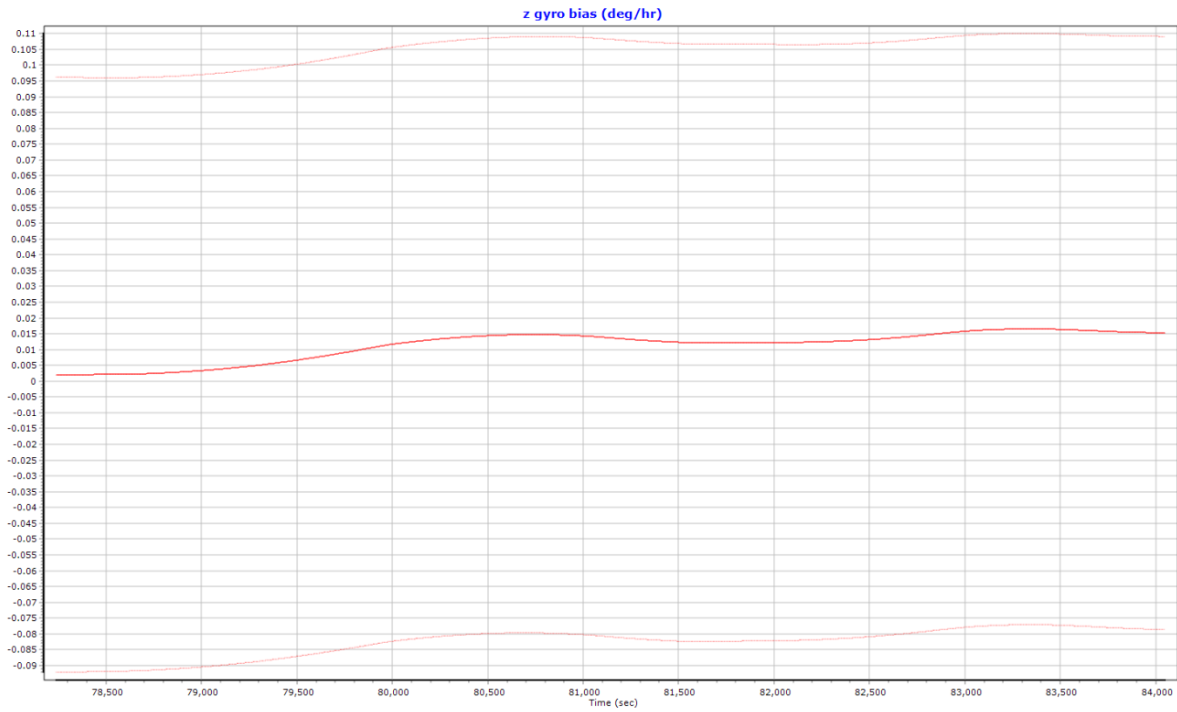




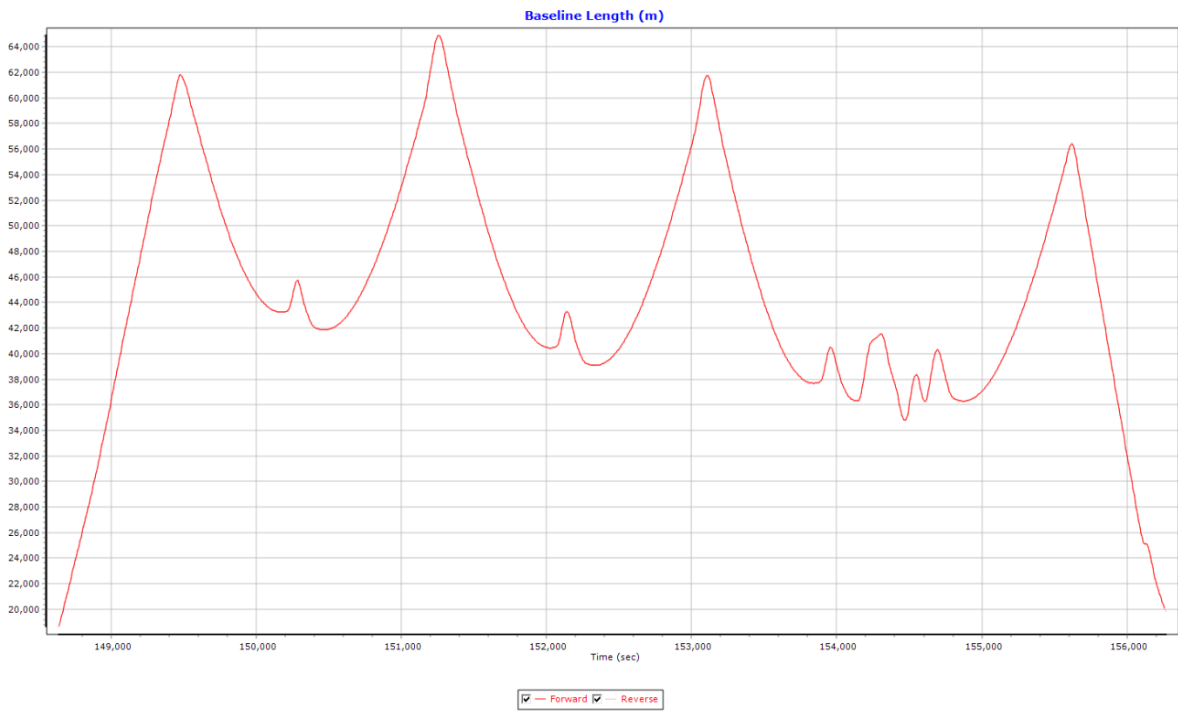
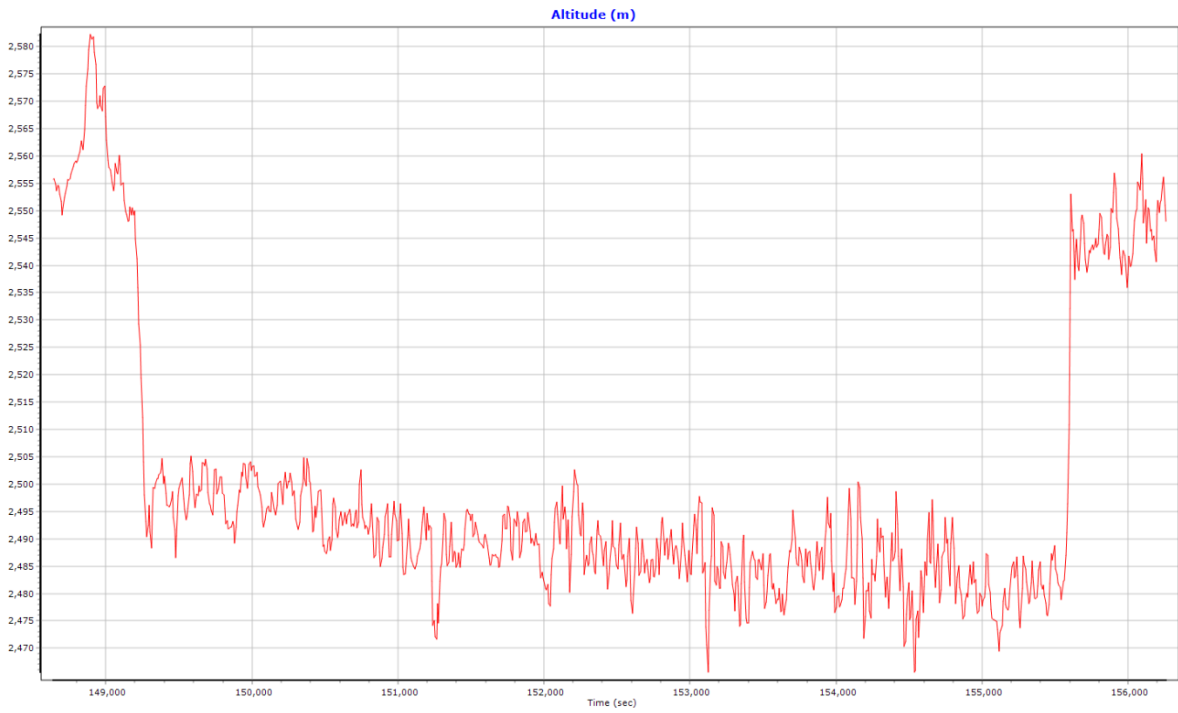


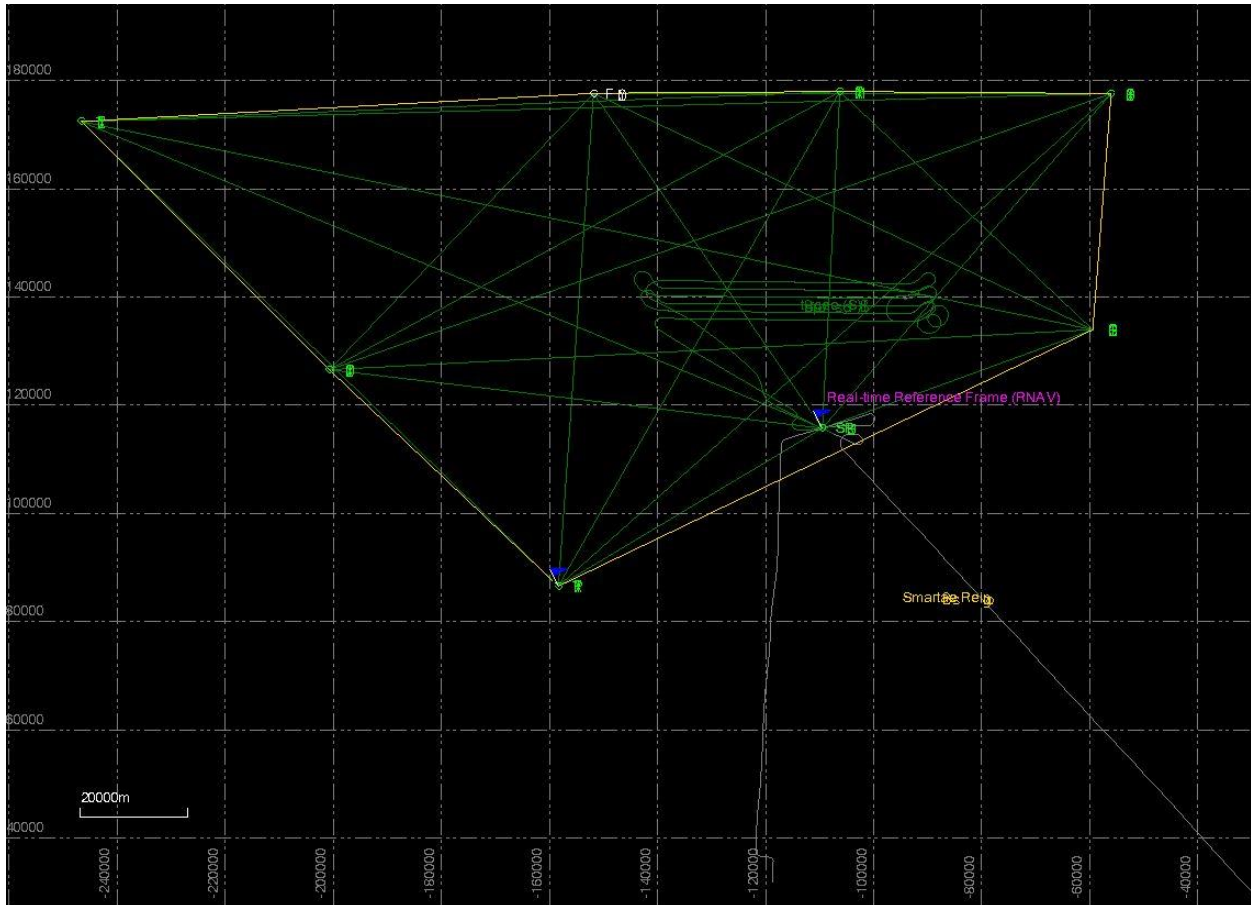






RBV18057A





Project Settings

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

Stabilized Mount to IMU Lever Arm

X	<input type="text" value="0.000 m"/>
Y	<input type="text" value="0.000 m"/>
Z	<input type="text" value="0.000 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="-0.031 m"/>
Y	<input type="text" value="0.004 m"/>
Z	<input type="text" value="-0.611 m"/>

Aircraft to Stabilized Mount Mounting Angles

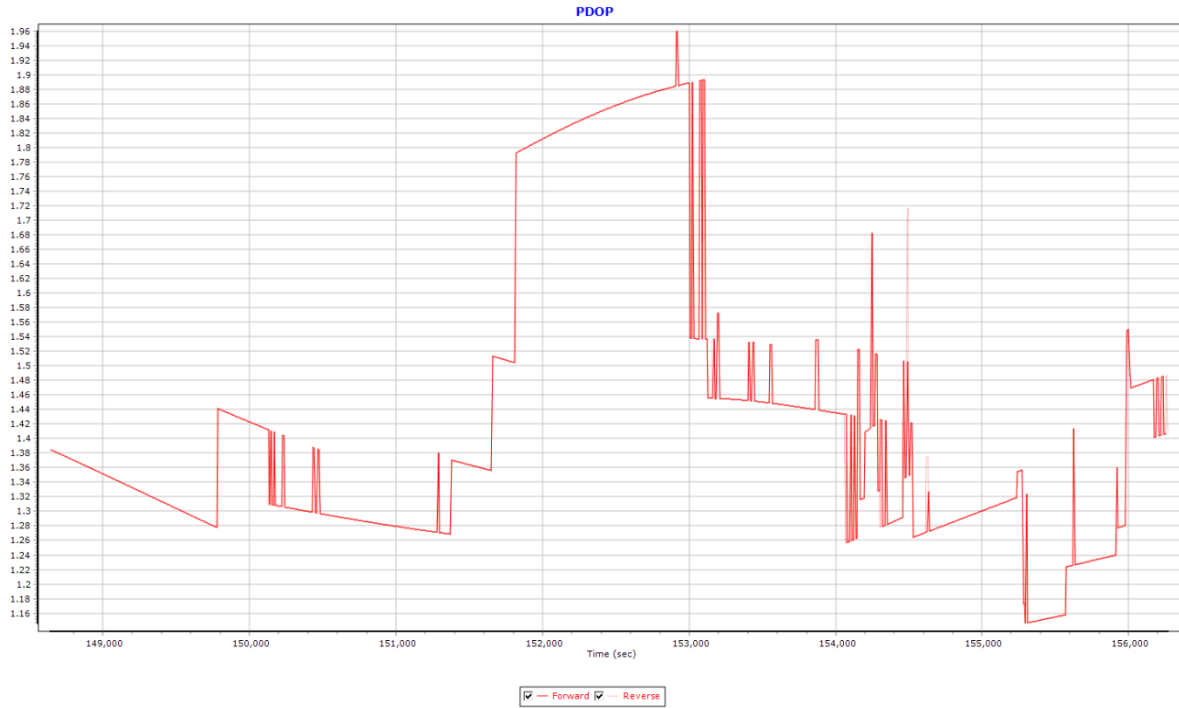
X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="0.000 deg"/>

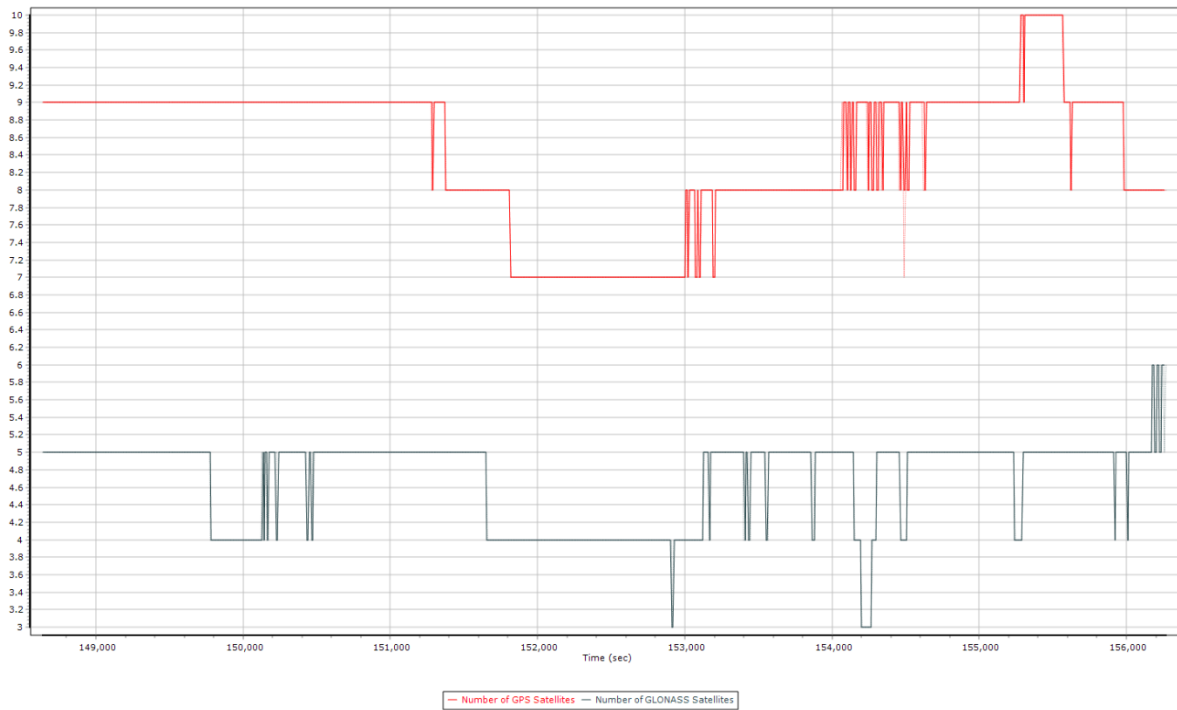
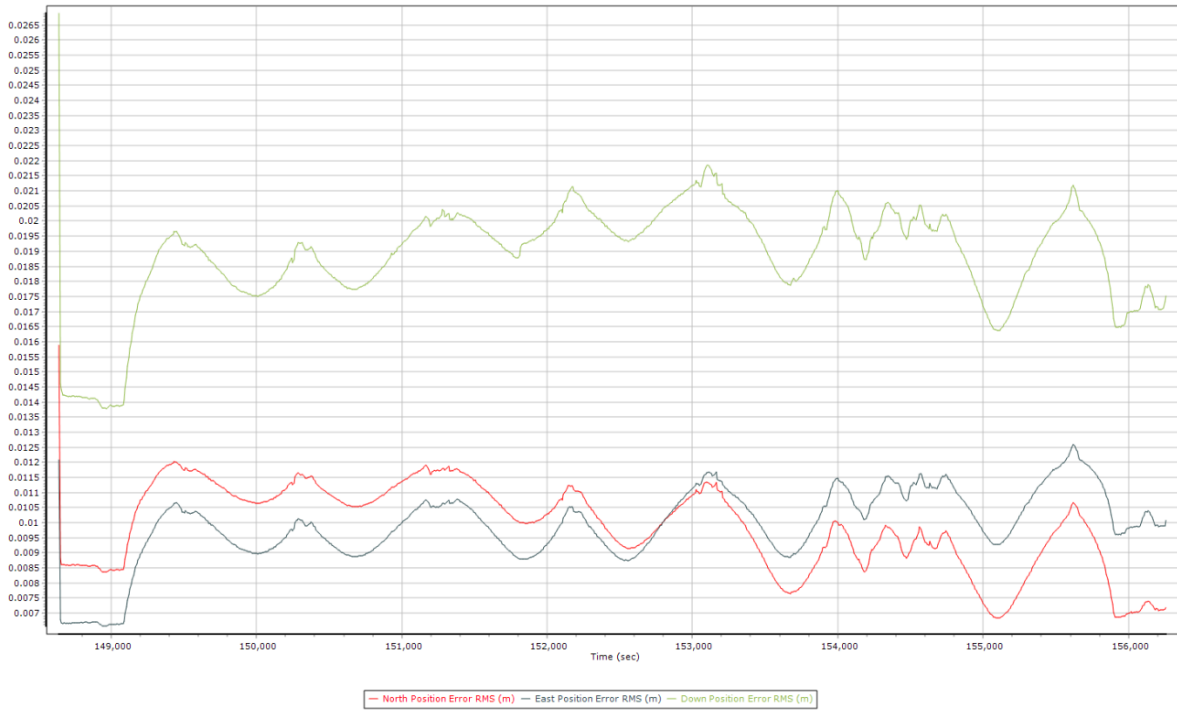
Standard Deviation

<3cm 10cm 50cm 1m 10m

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

OK Cancel







Project Settings [X]

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

Timing

Start: 148638.259 Data Incr. (sec) ▲

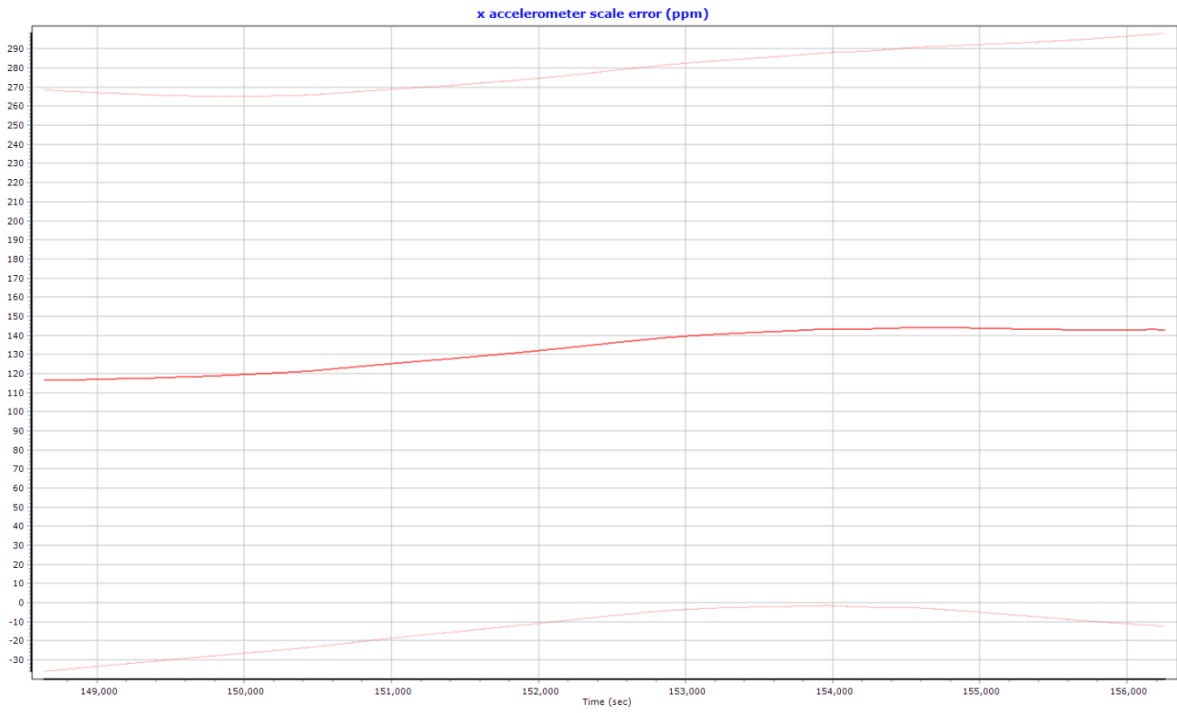
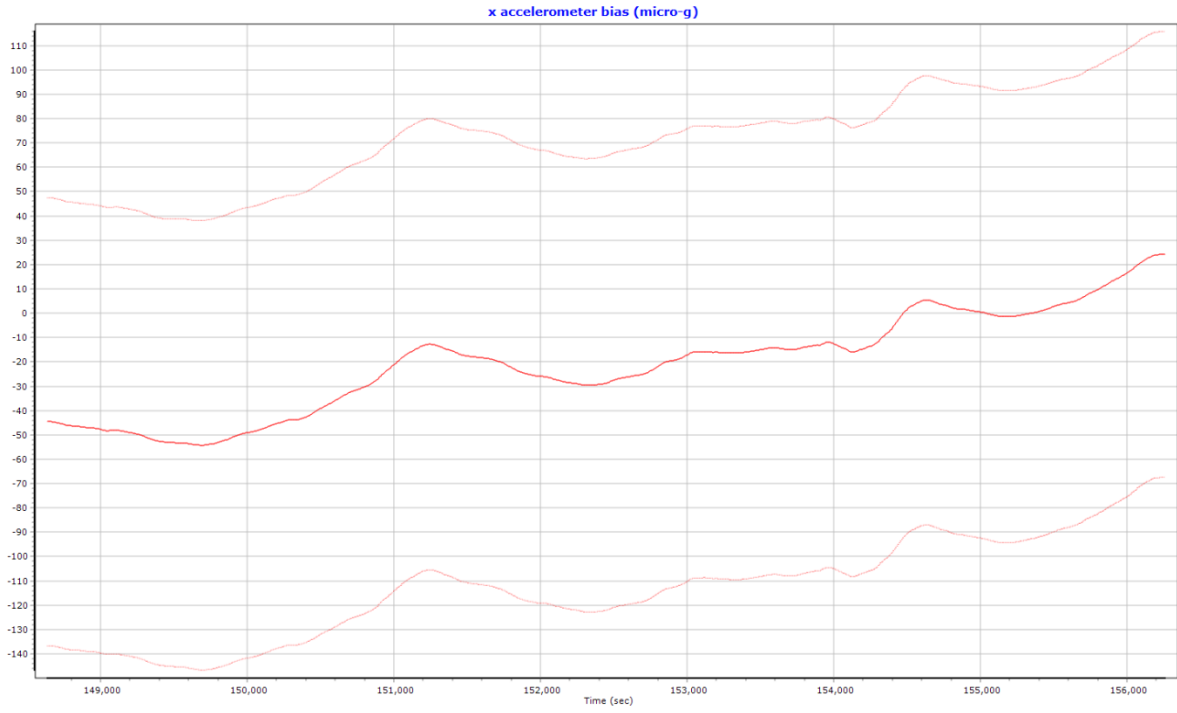
End: 156270.011 Output Record 0.005000

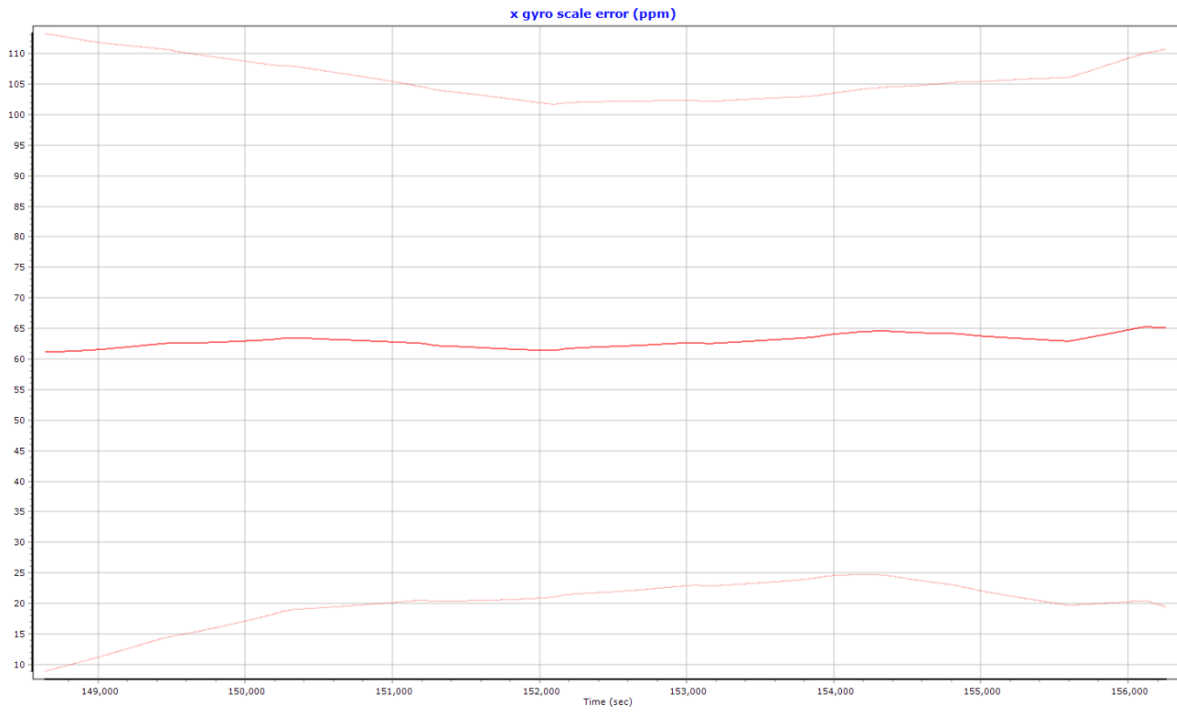
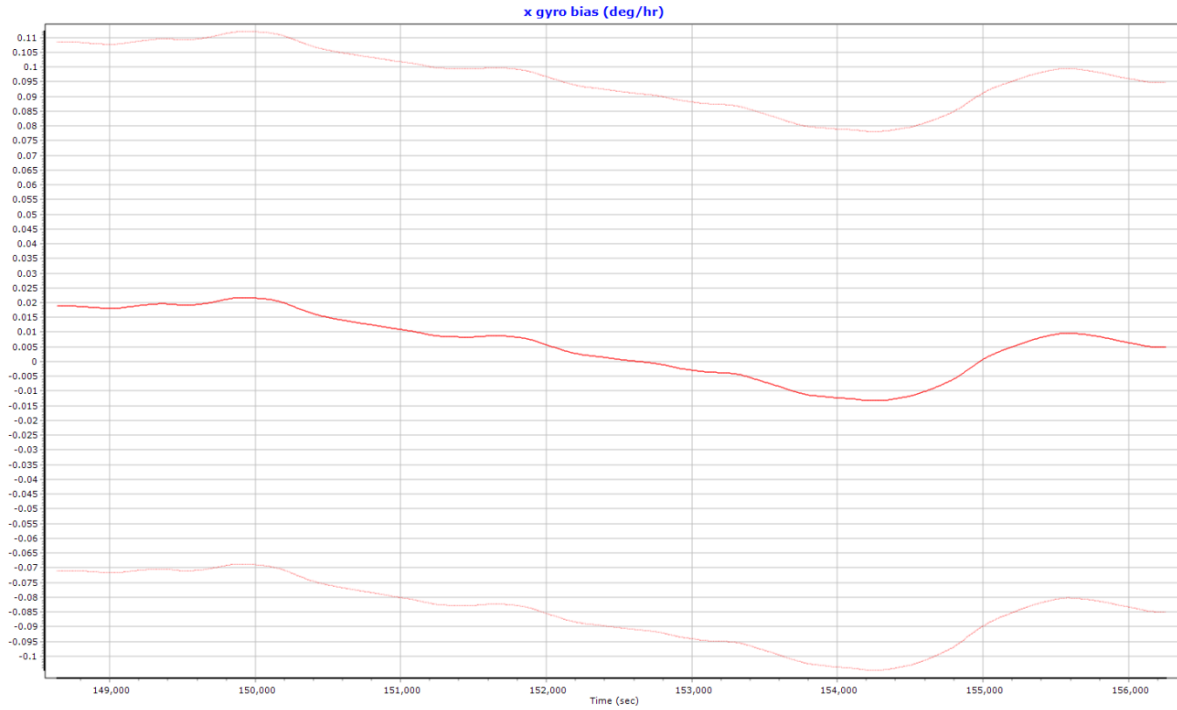
Entire time interval IMU 0.005000

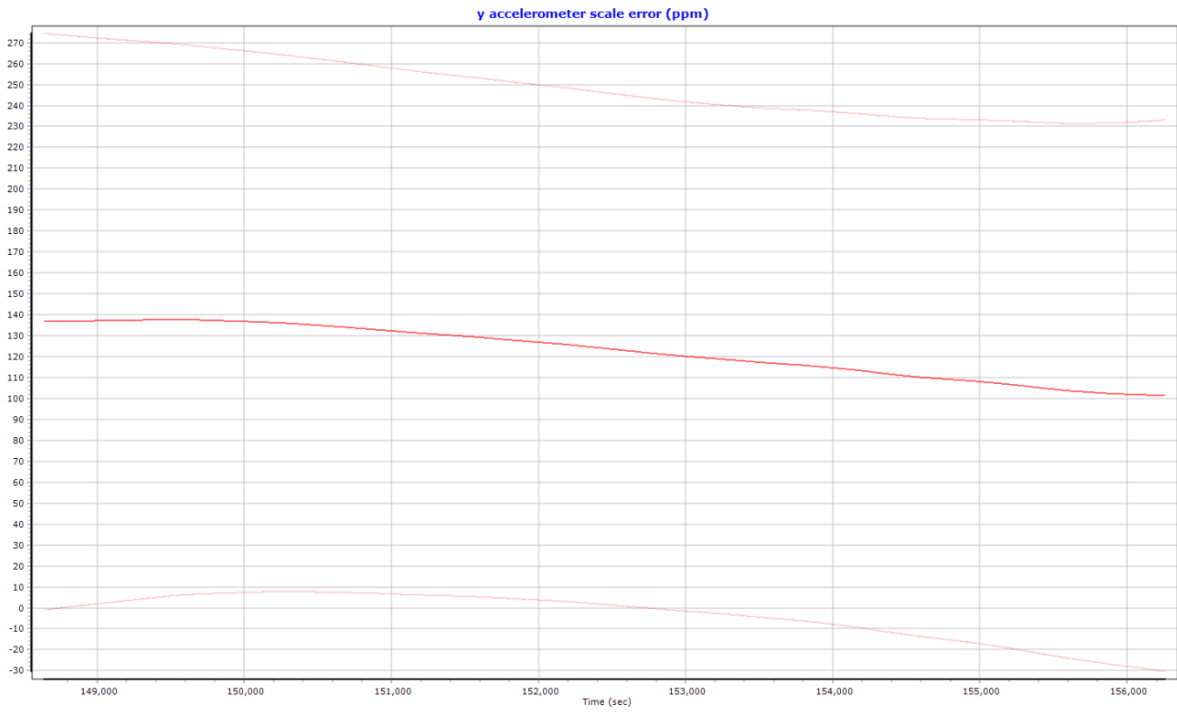
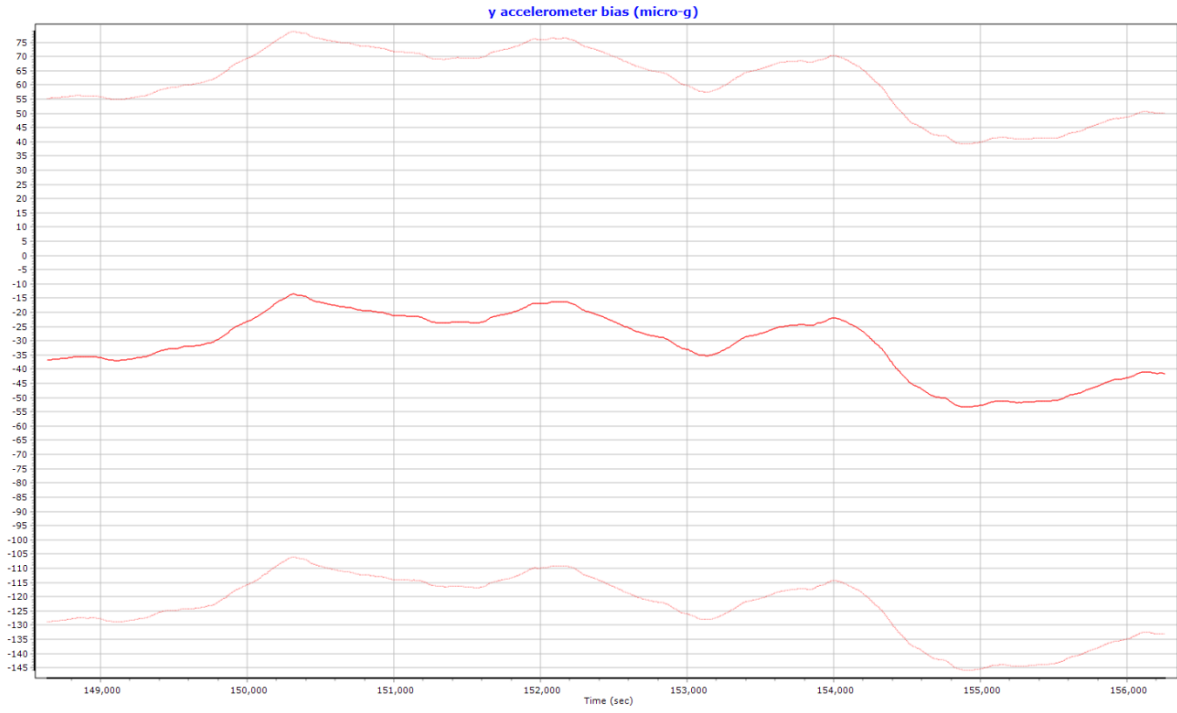
Seconds of start week Primary GNSS 1.000000 ▼

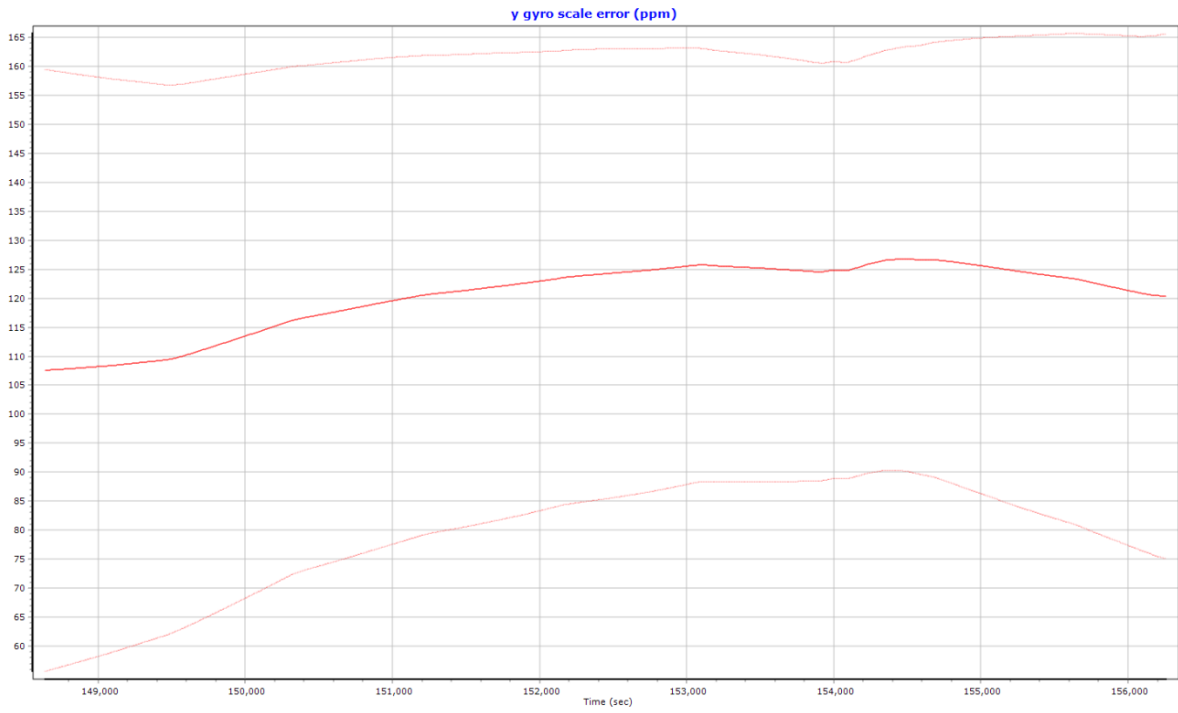
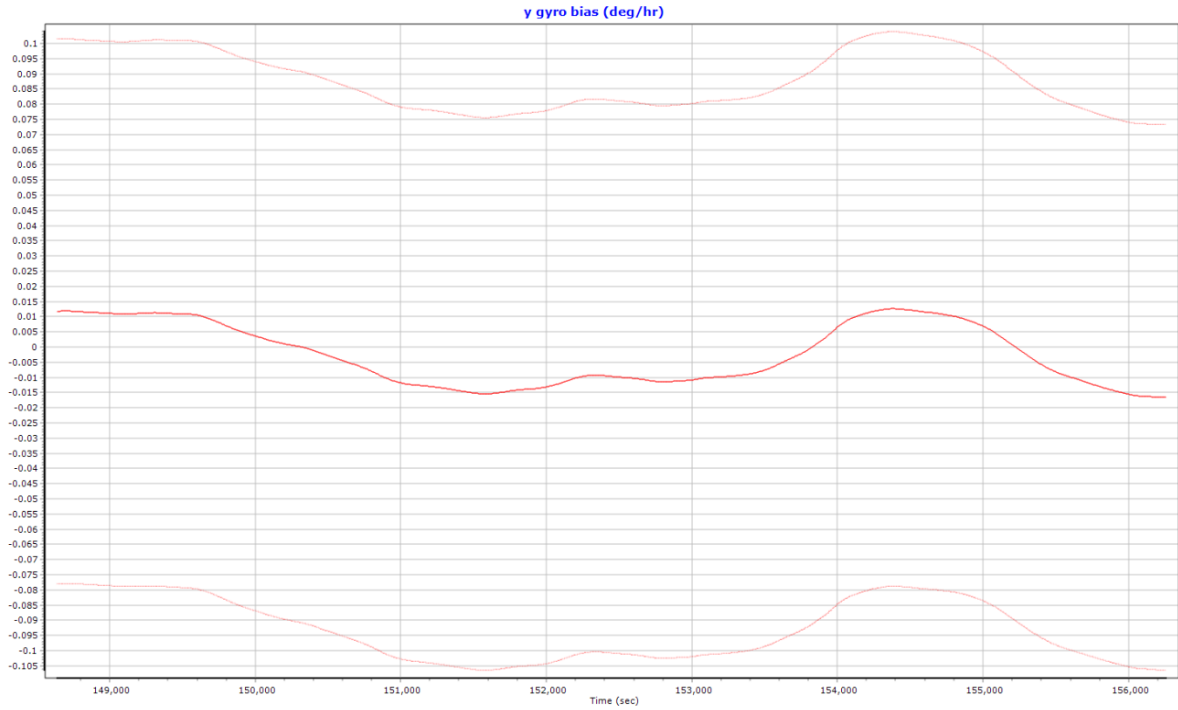
UTC Offset: 18.000

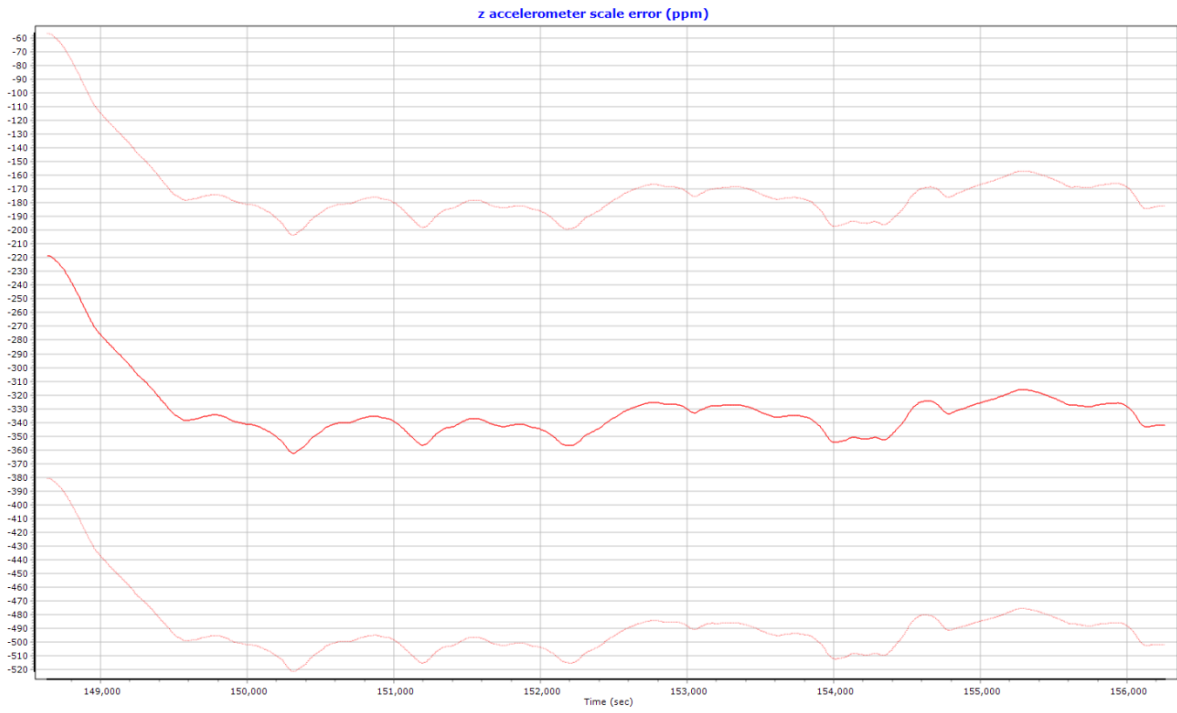
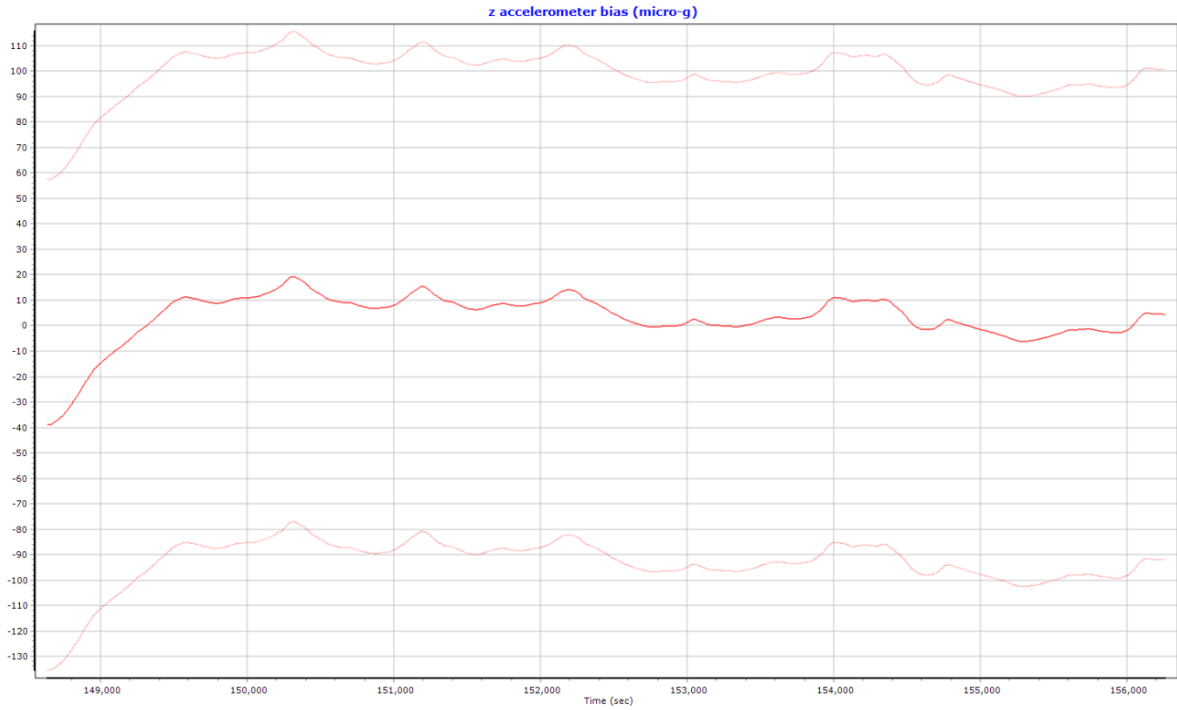
OK Cancel

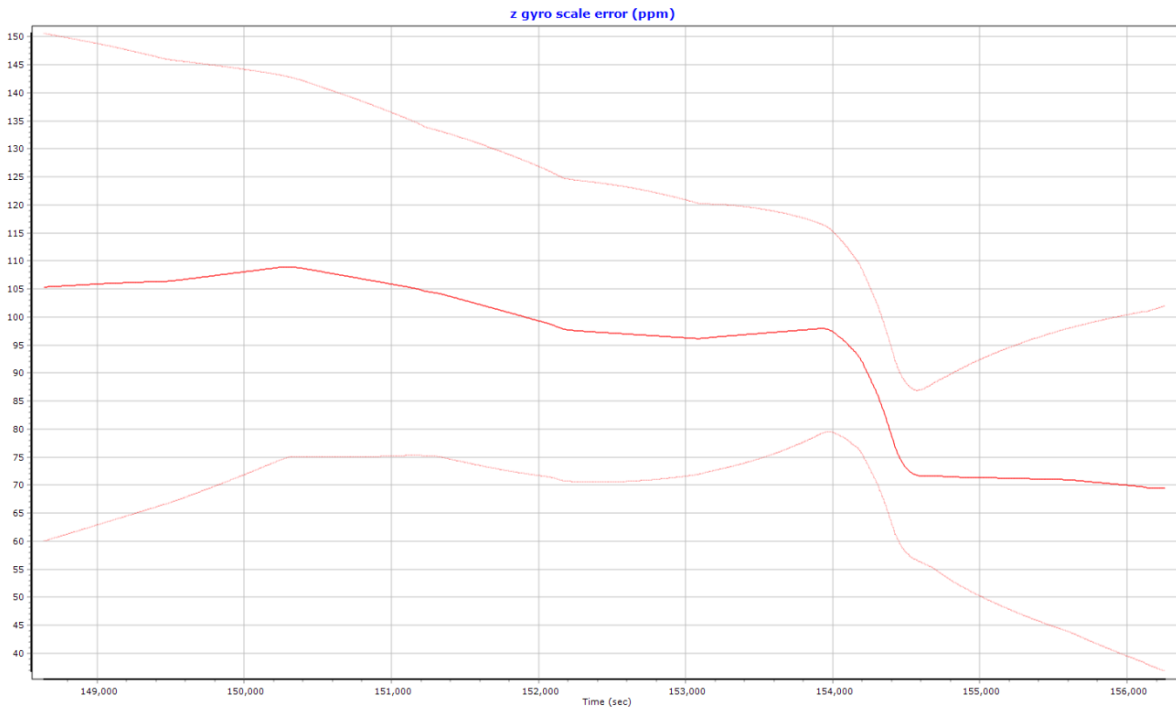
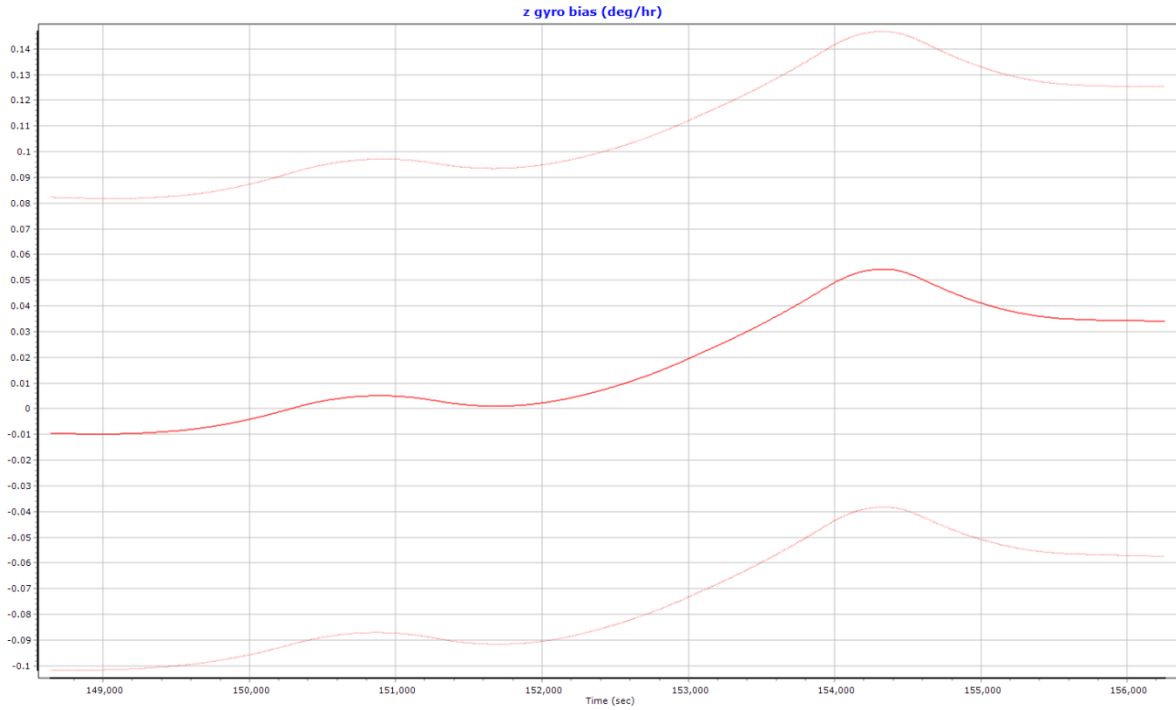




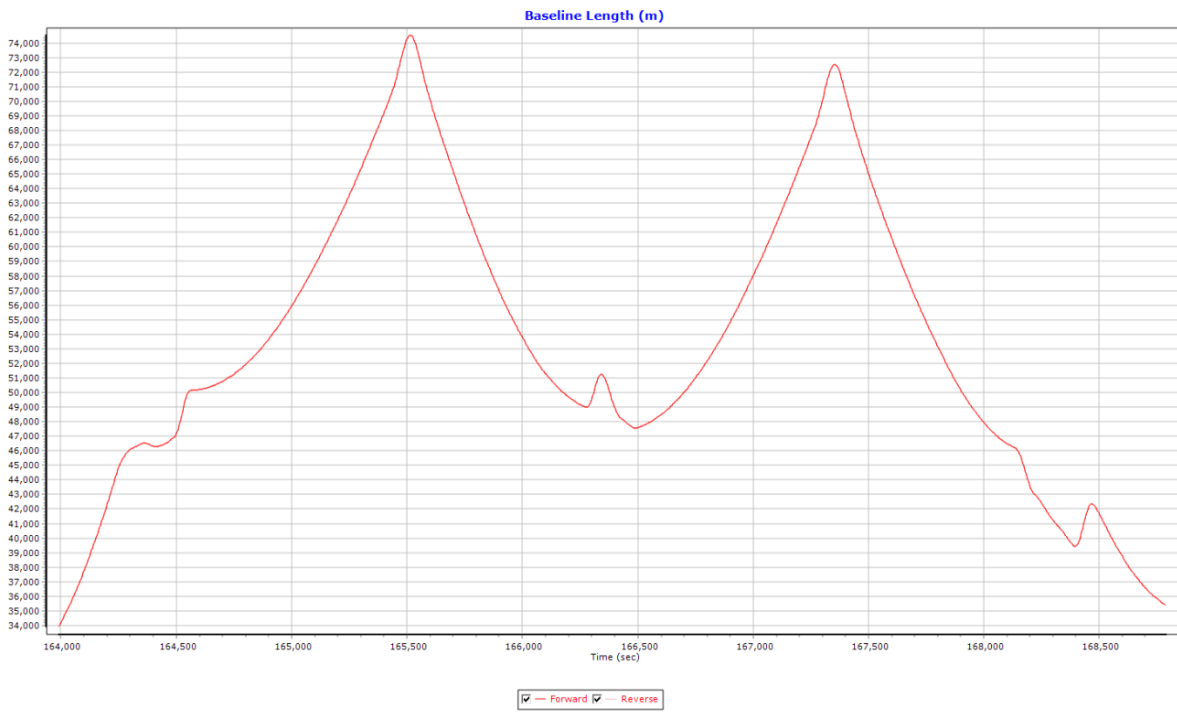
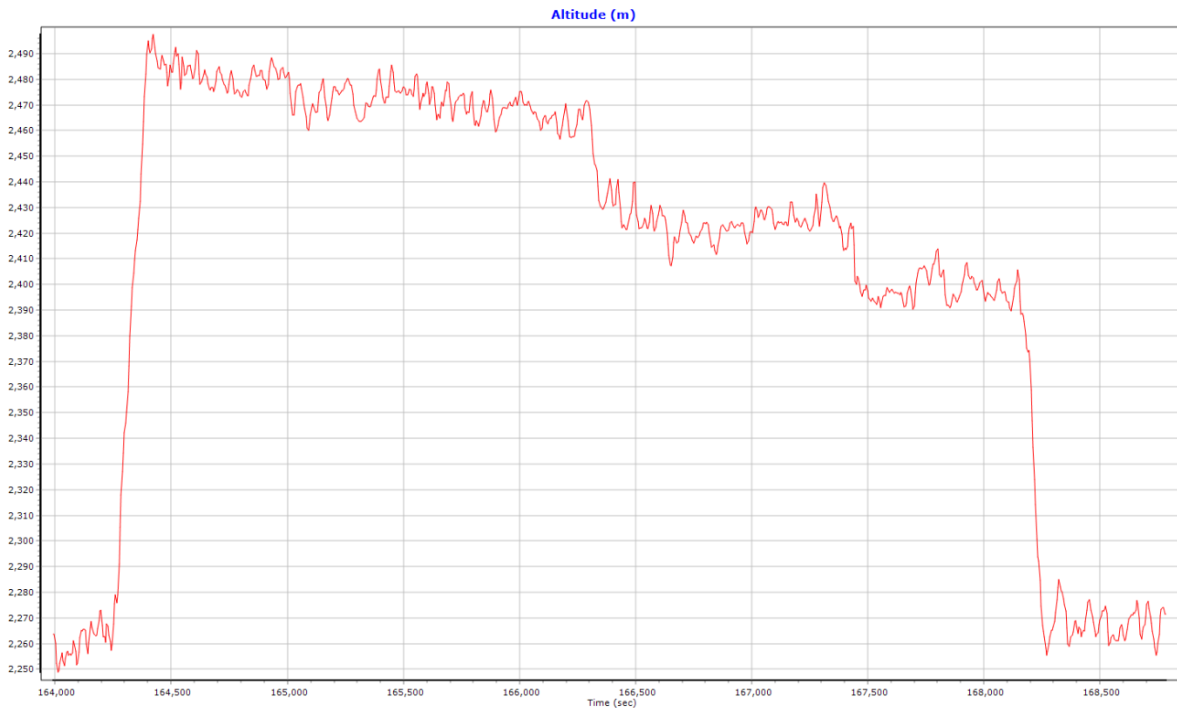


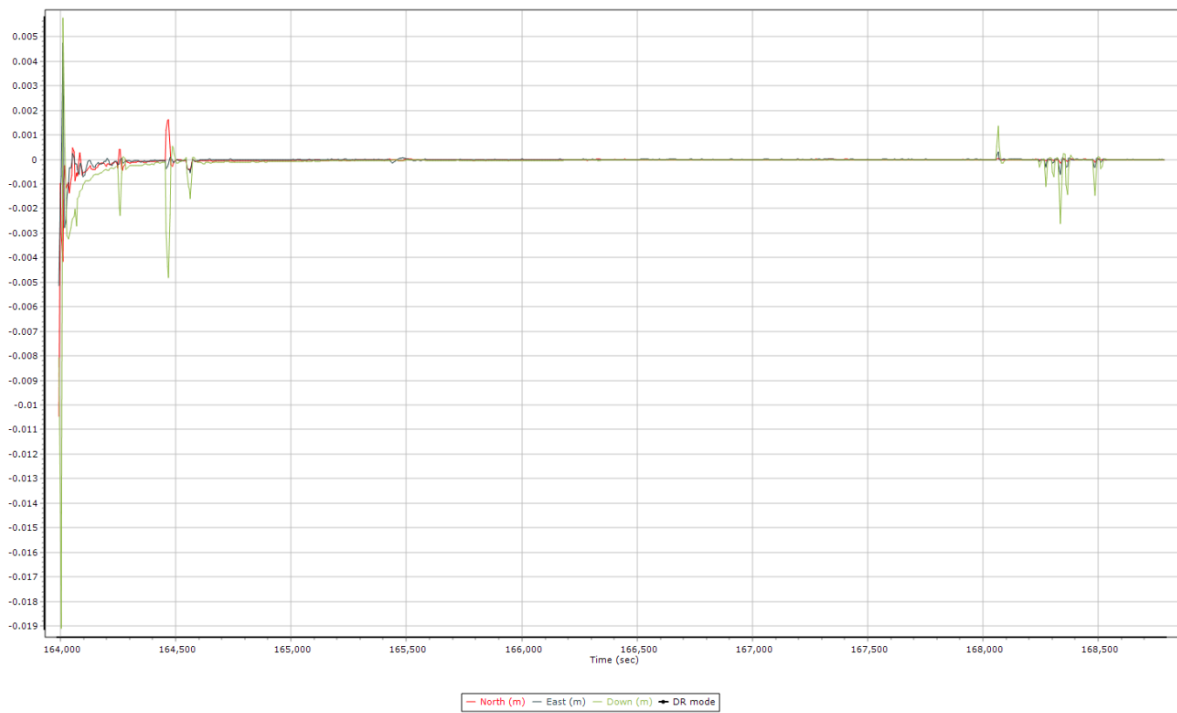
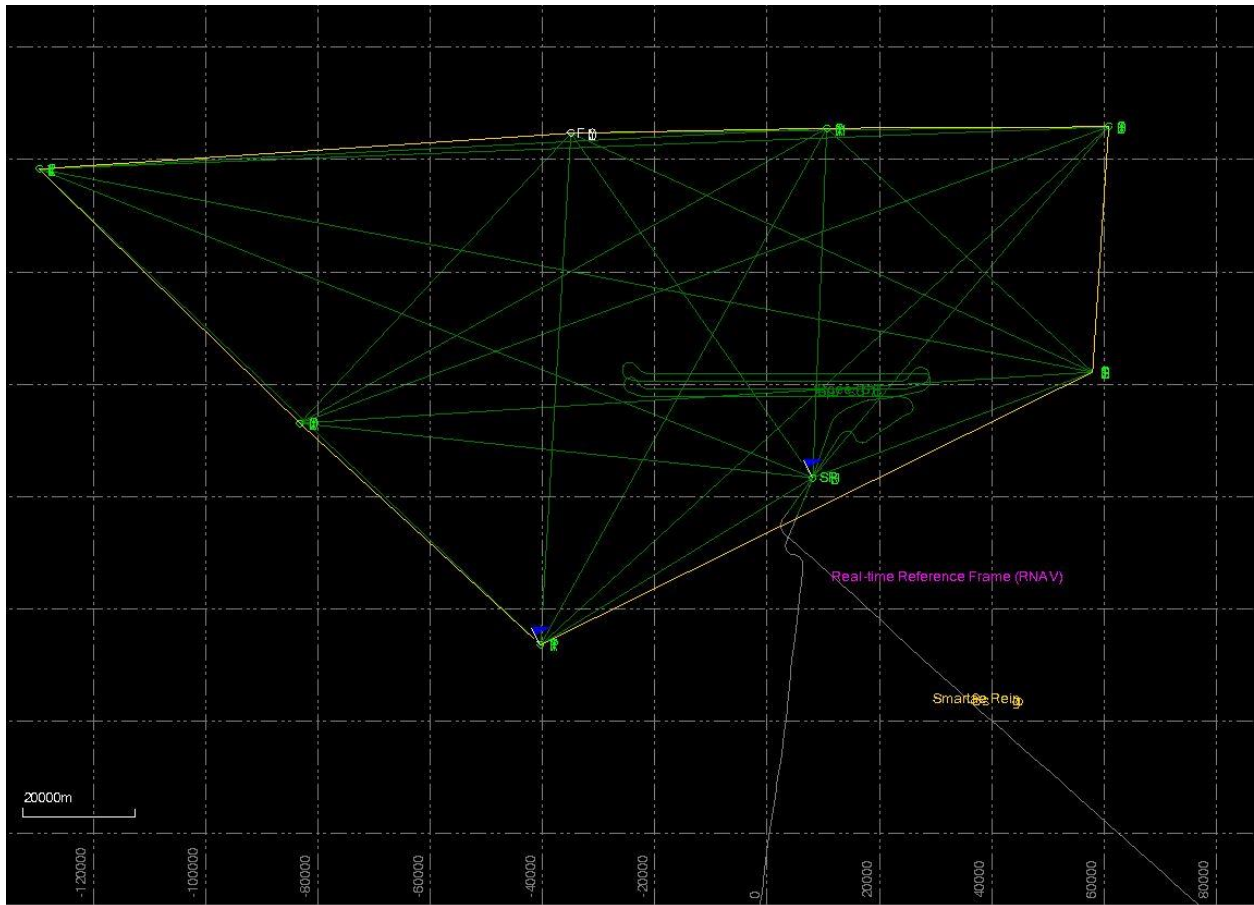






RBV18057B





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	0.000 m
Y	0.000 m
Z	0.000 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	-0.031 m
Y	0.004 m
Z	-0.611 m

Aircraft to Stabilized Mount Mounting Angles

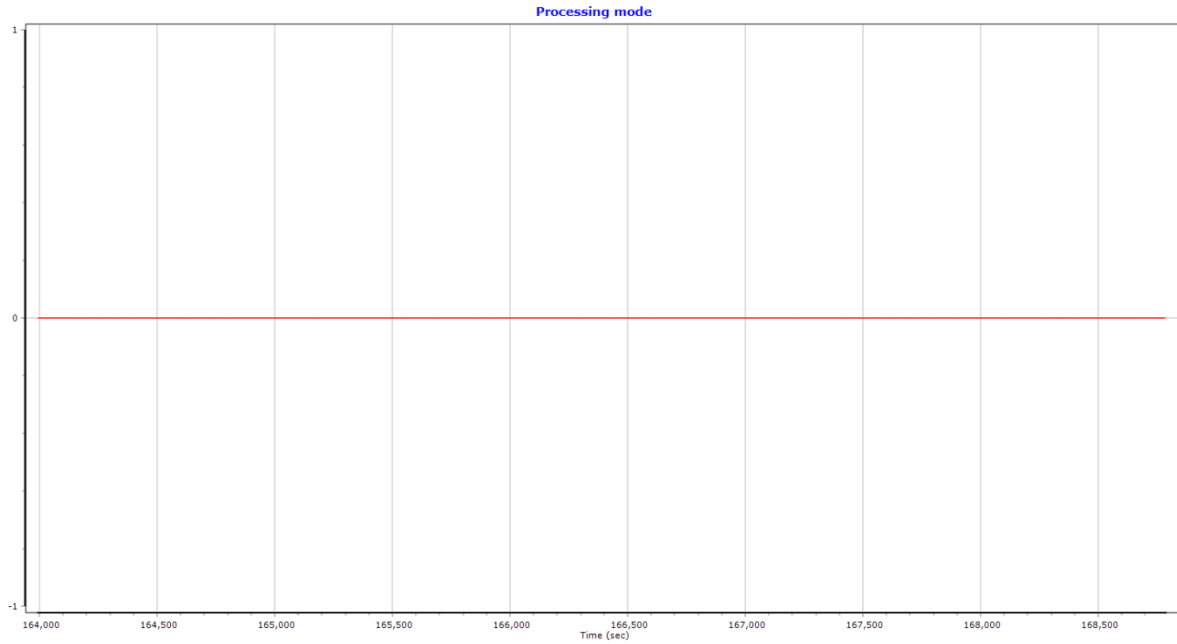
X	0.000 deg
Y	0.000 deg
Z	0.000 deg

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

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

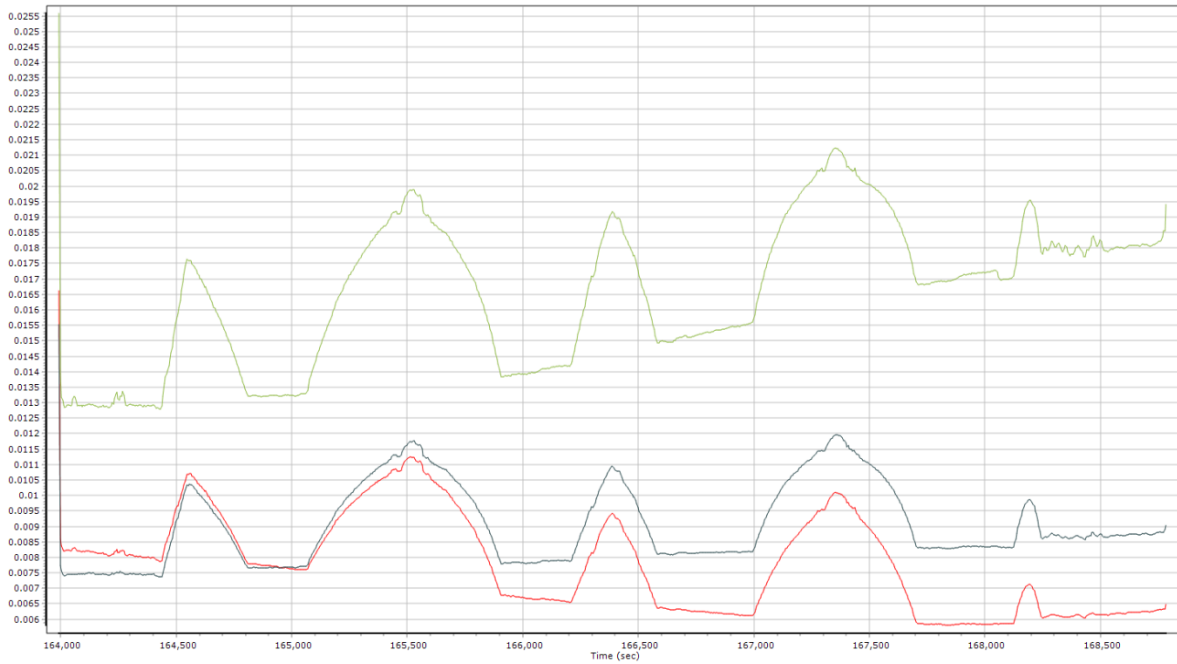
OK Cancel



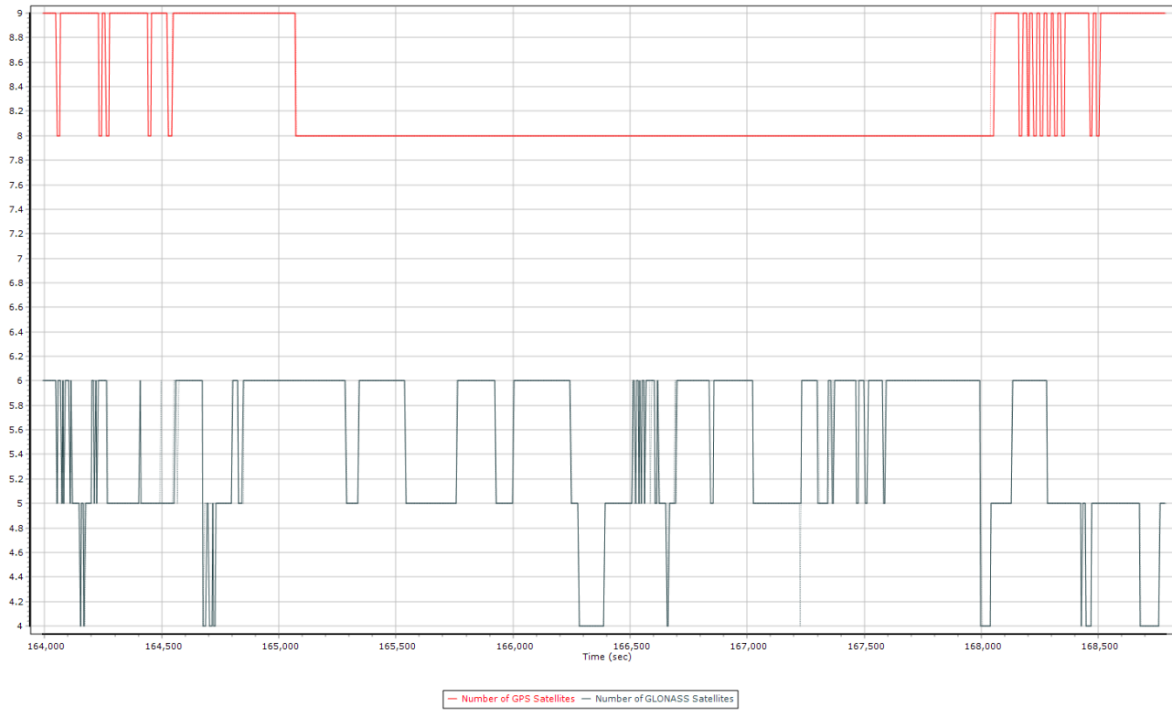


Forward Reverse

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



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



Project Settings [X]

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

Timing

Start: 163989.209 Data Incr. (sec) ▲

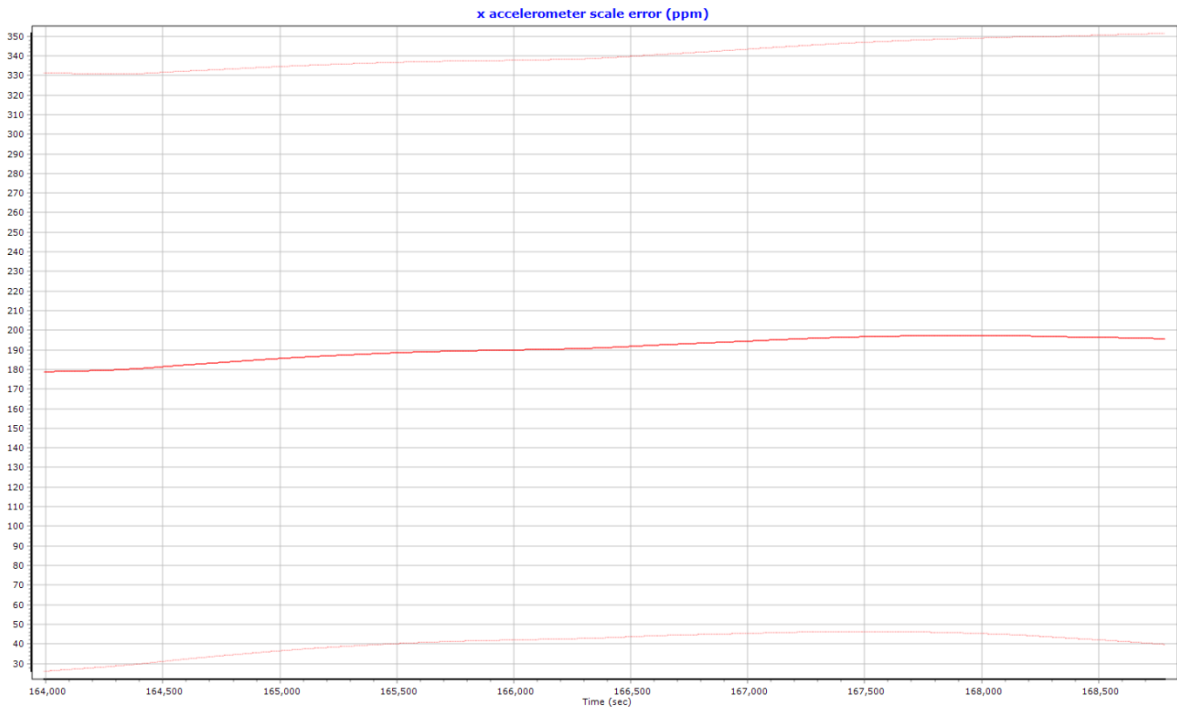
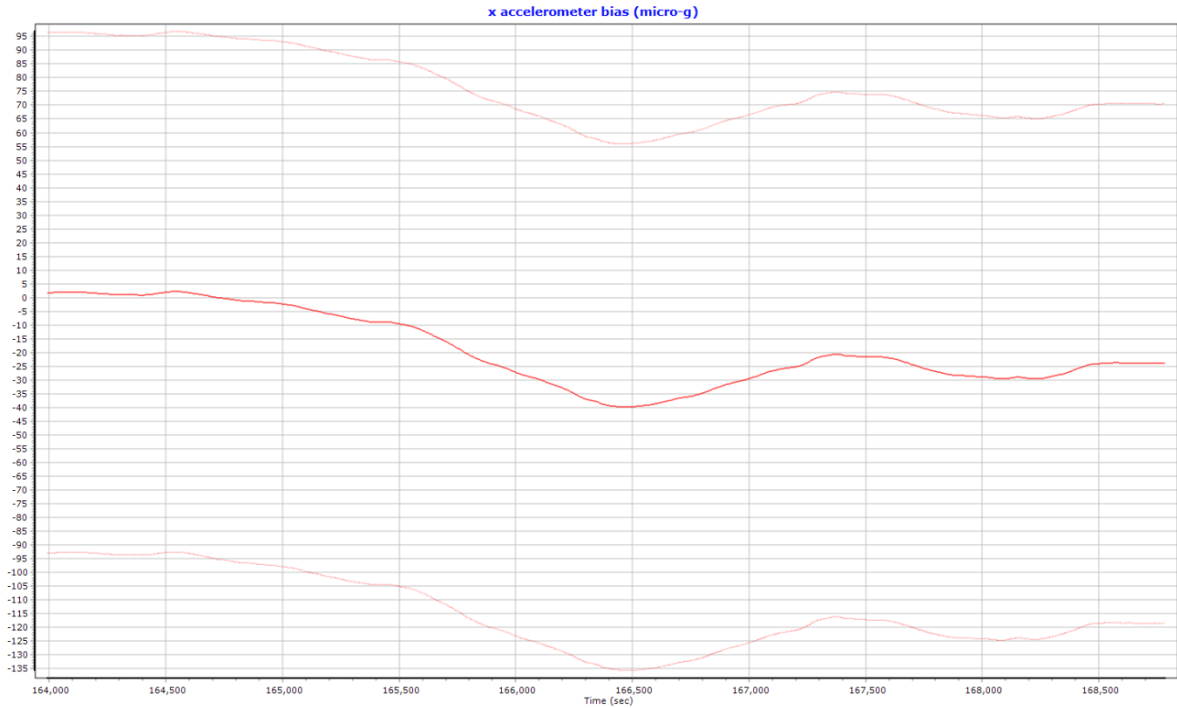
End: 168790.328 Output Record 0.005000

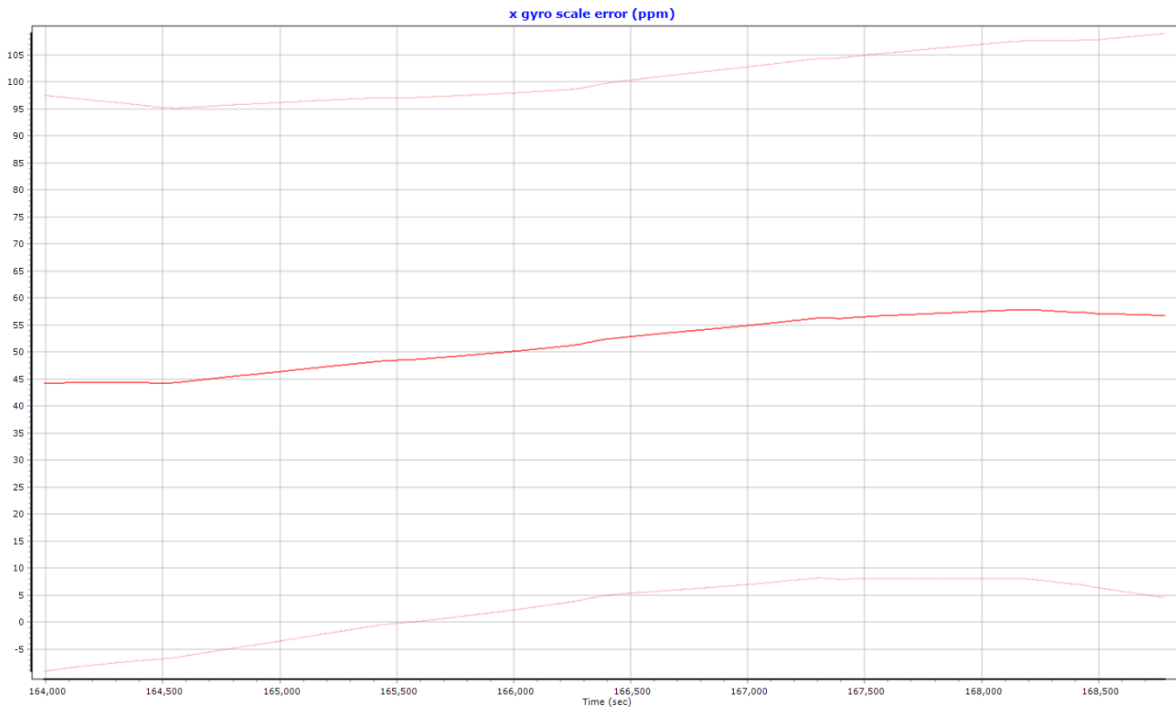
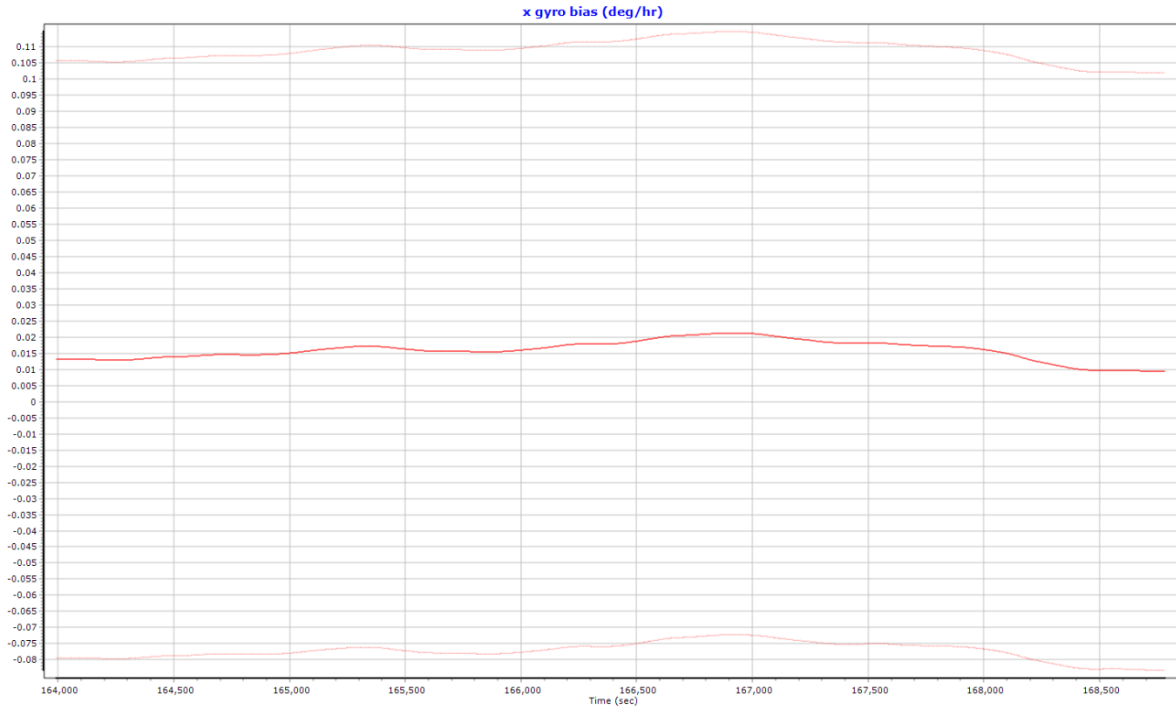
Entire time interval IMU 0.005000

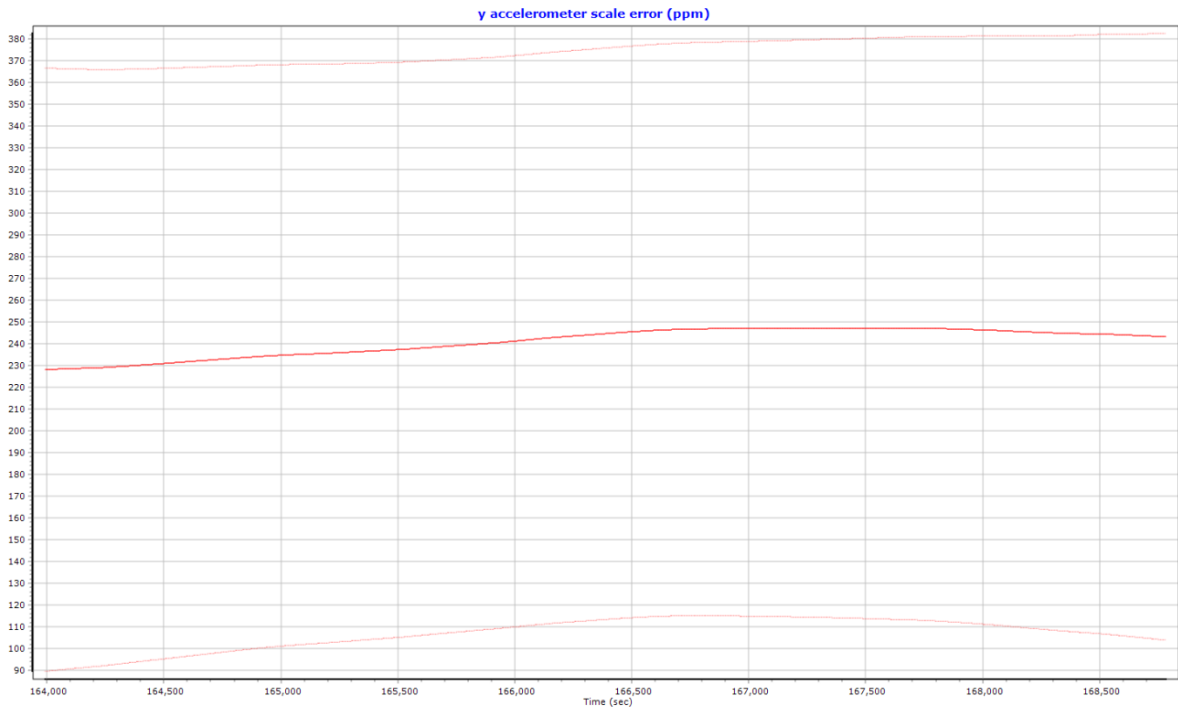
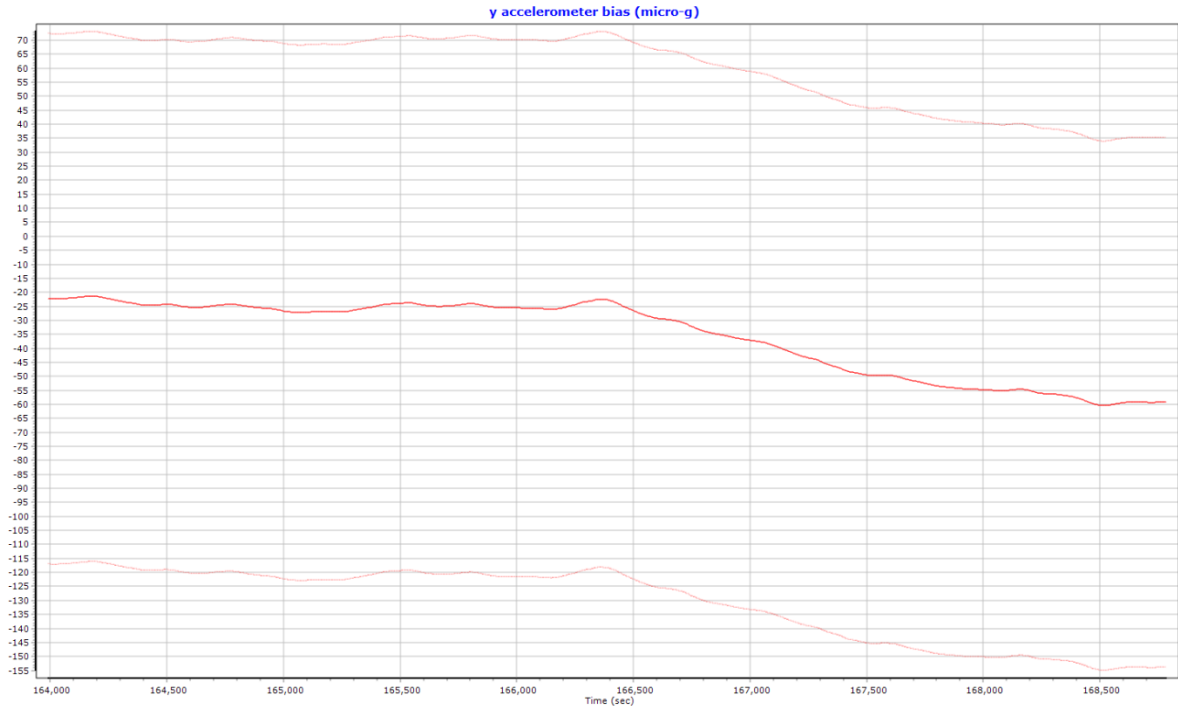
Seconds of start week Primary GNSS 1.000000 ▼

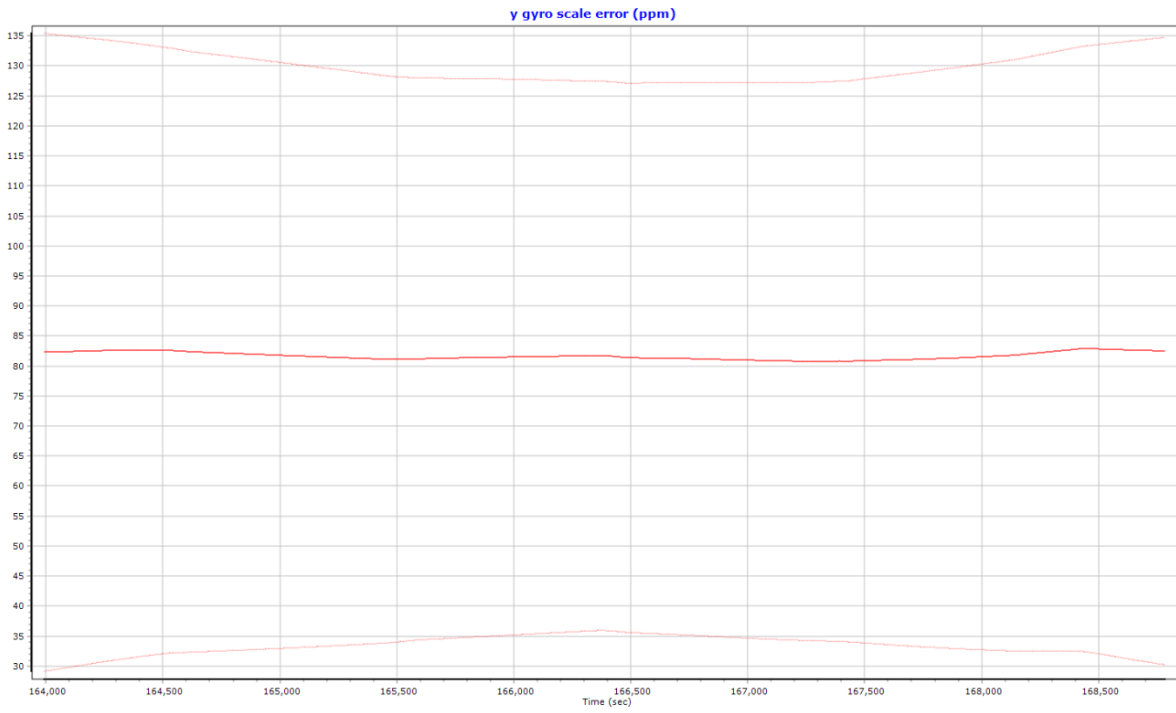
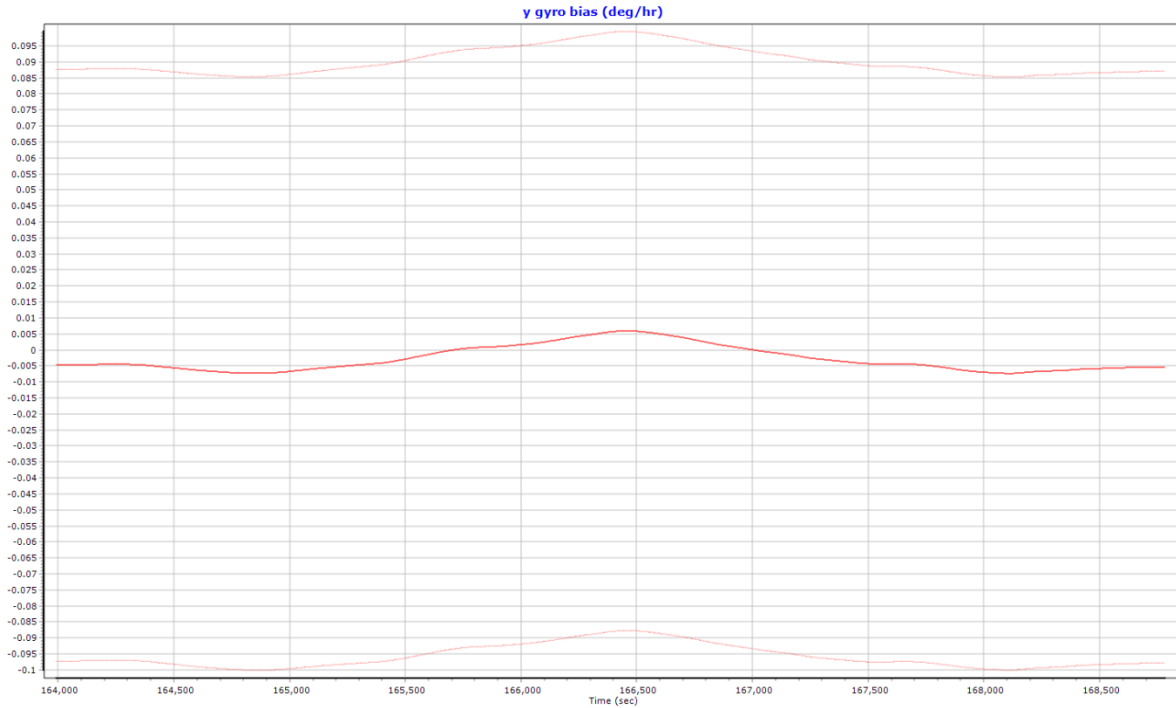
UTC Offset: 18.000

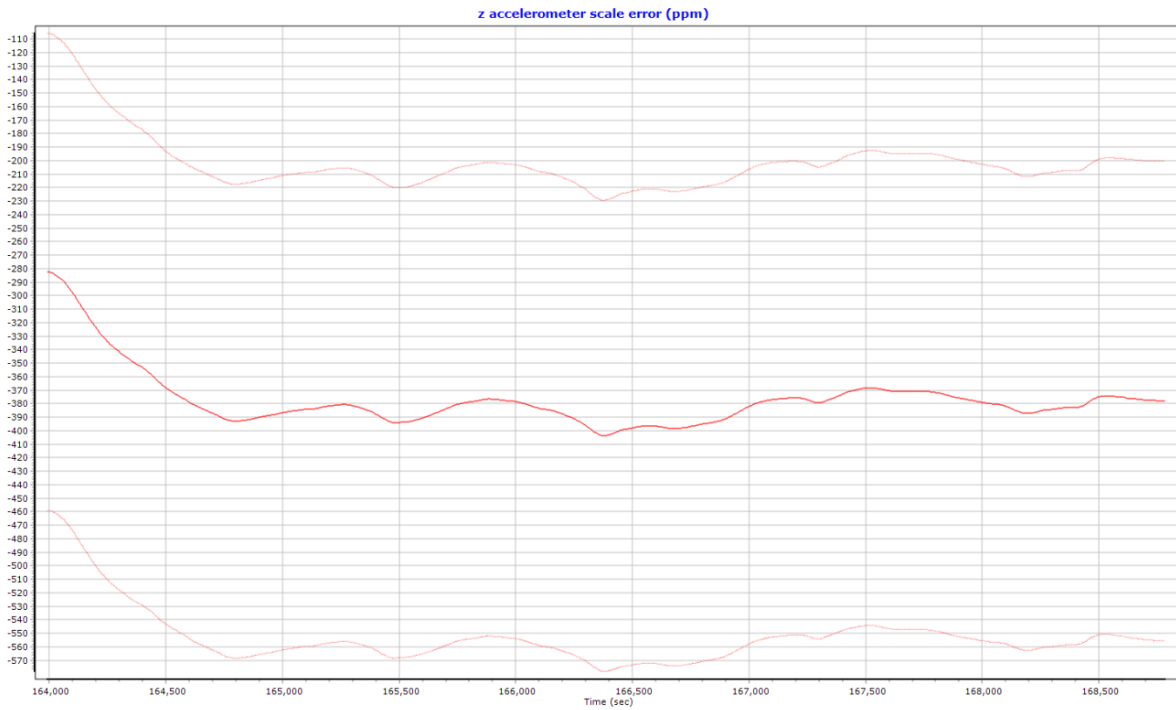
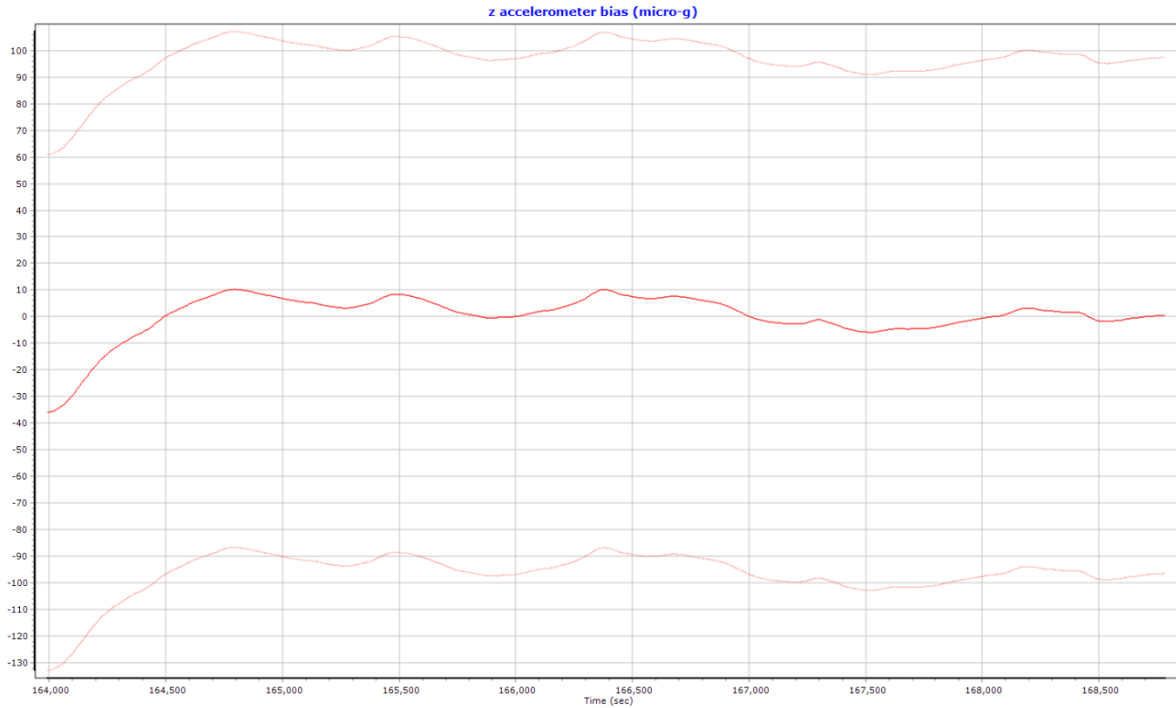
OK Cancel

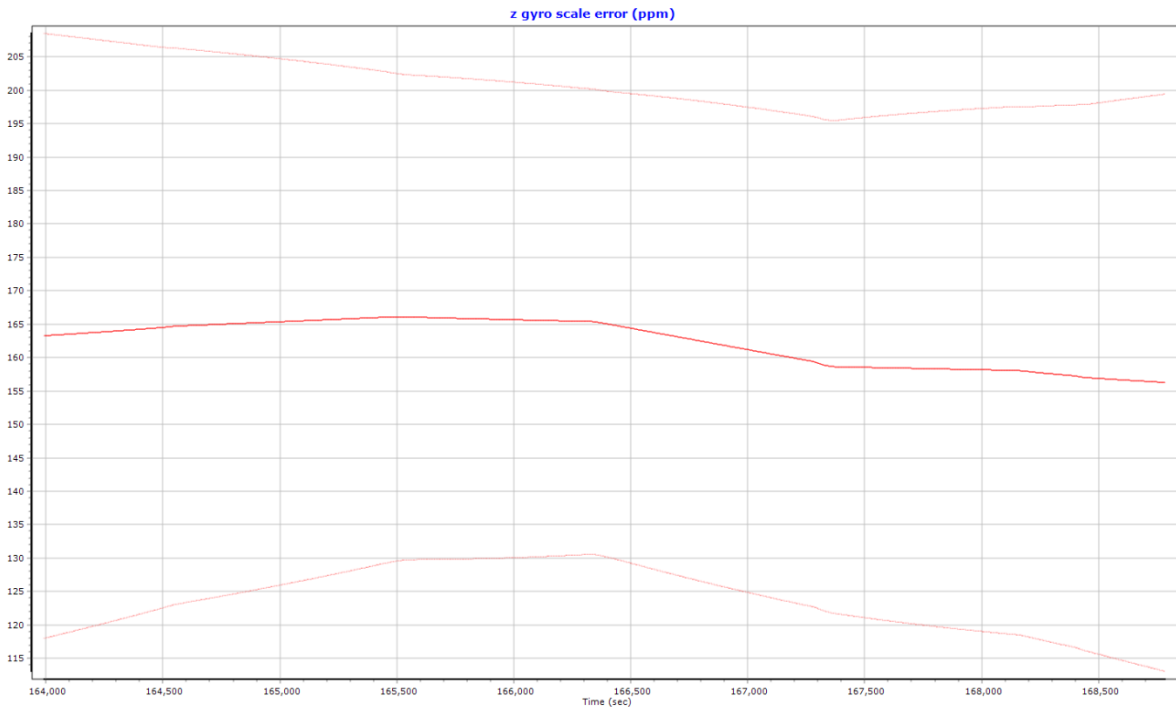
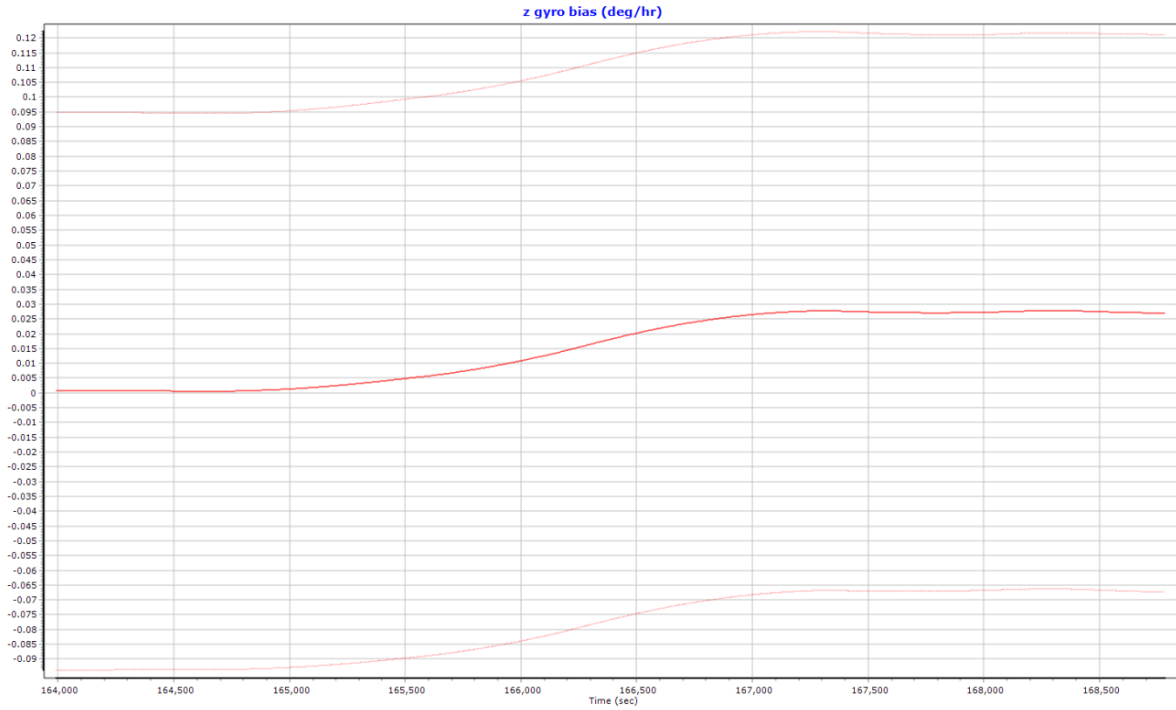




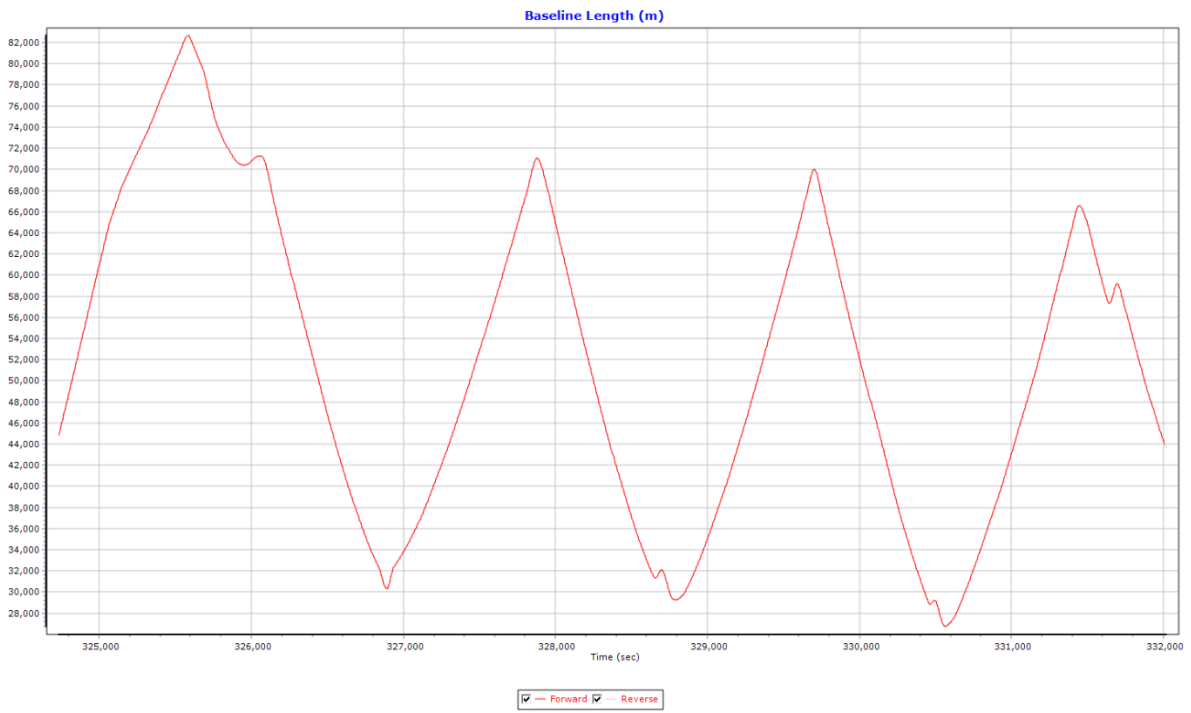
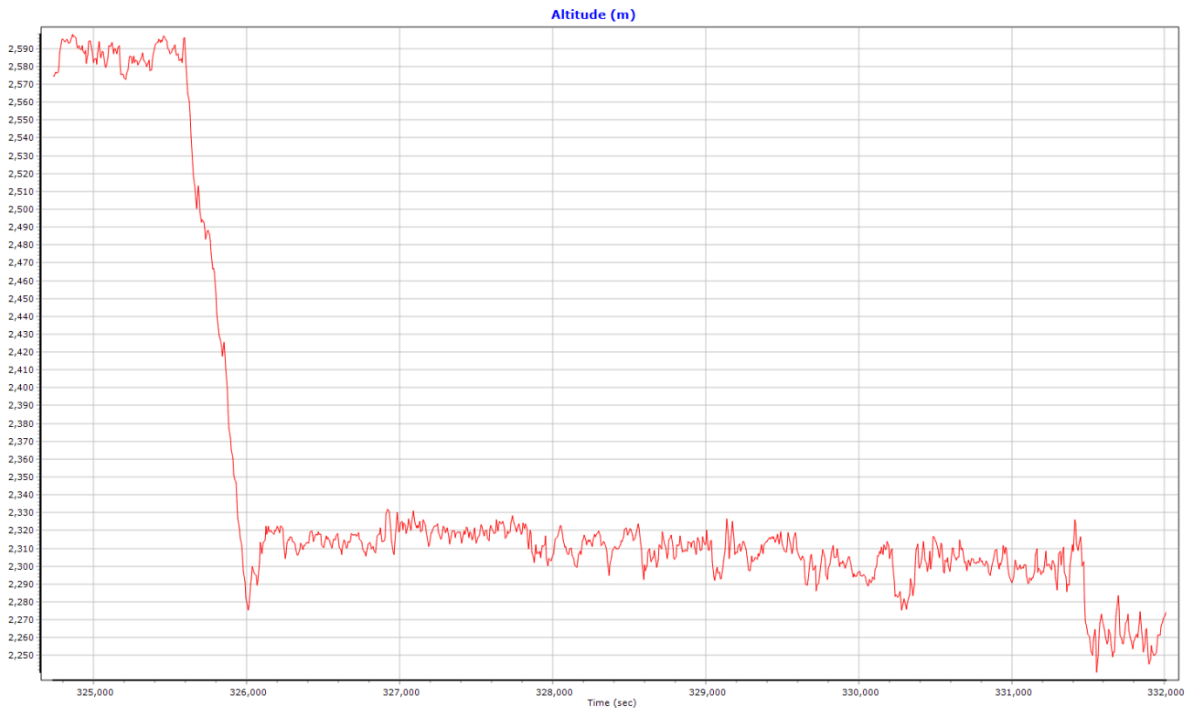


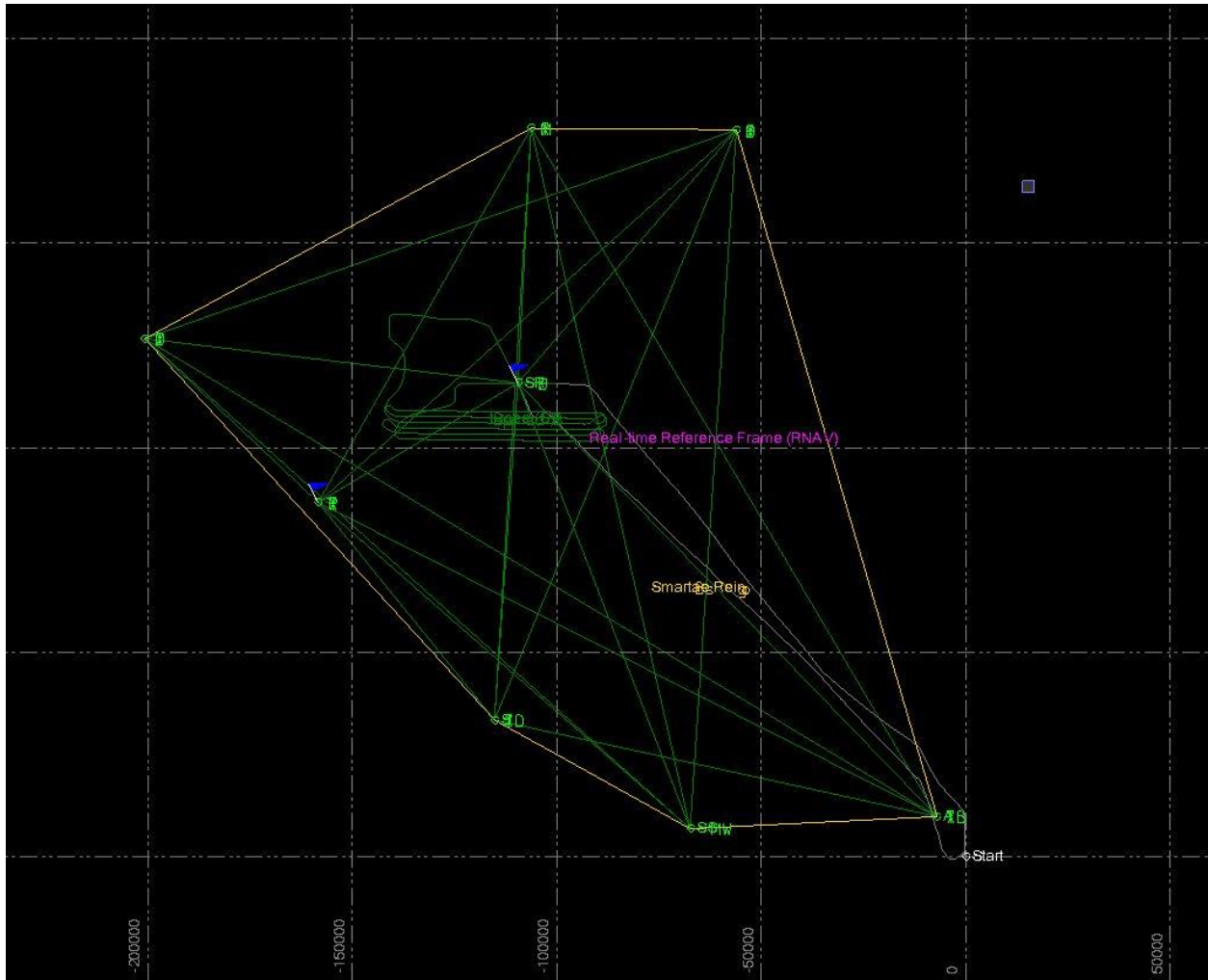


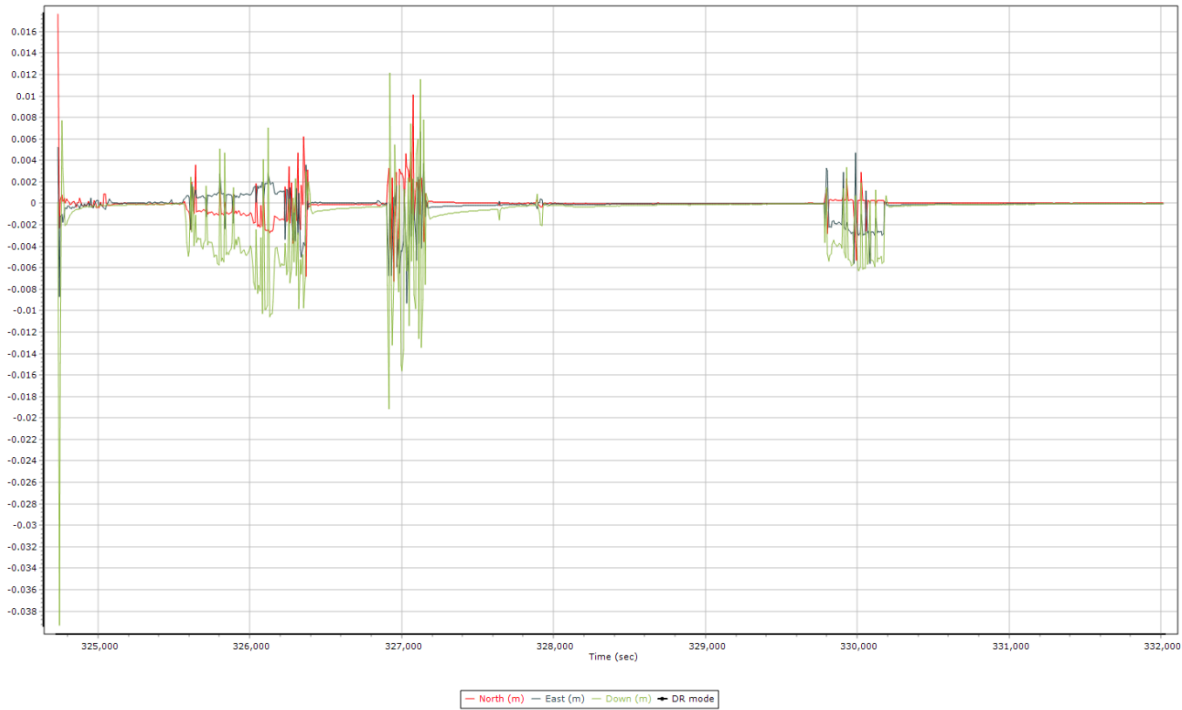




RBV18059A







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:

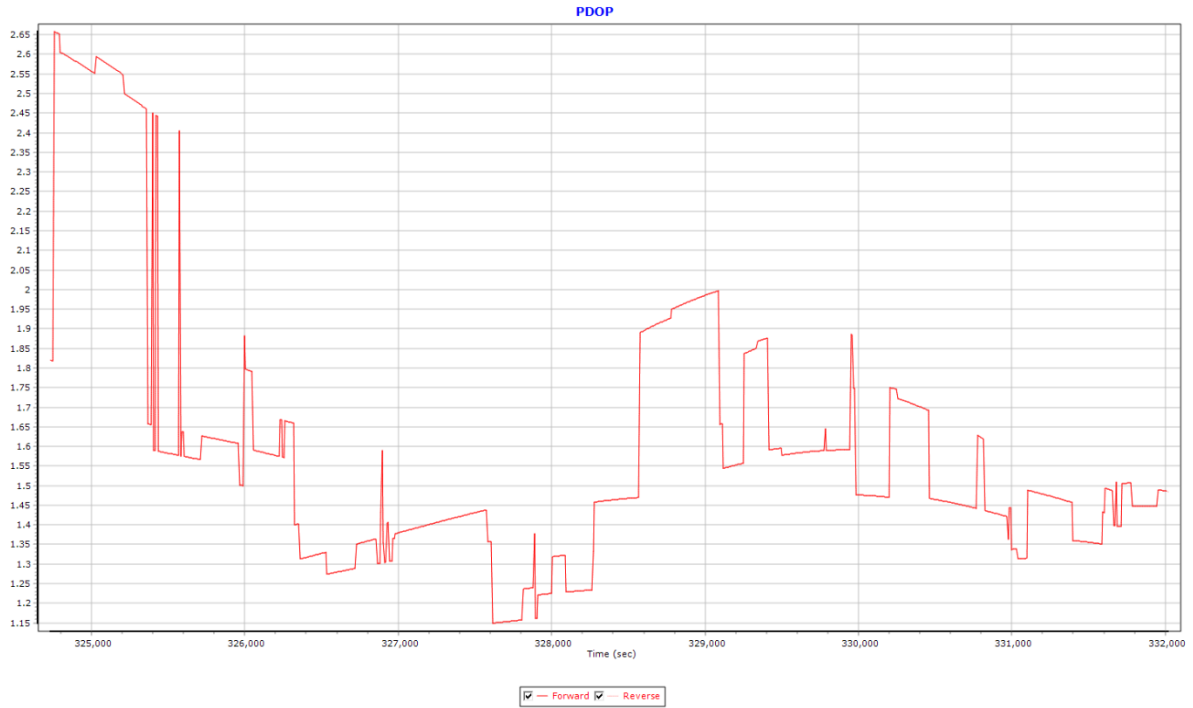
Y:

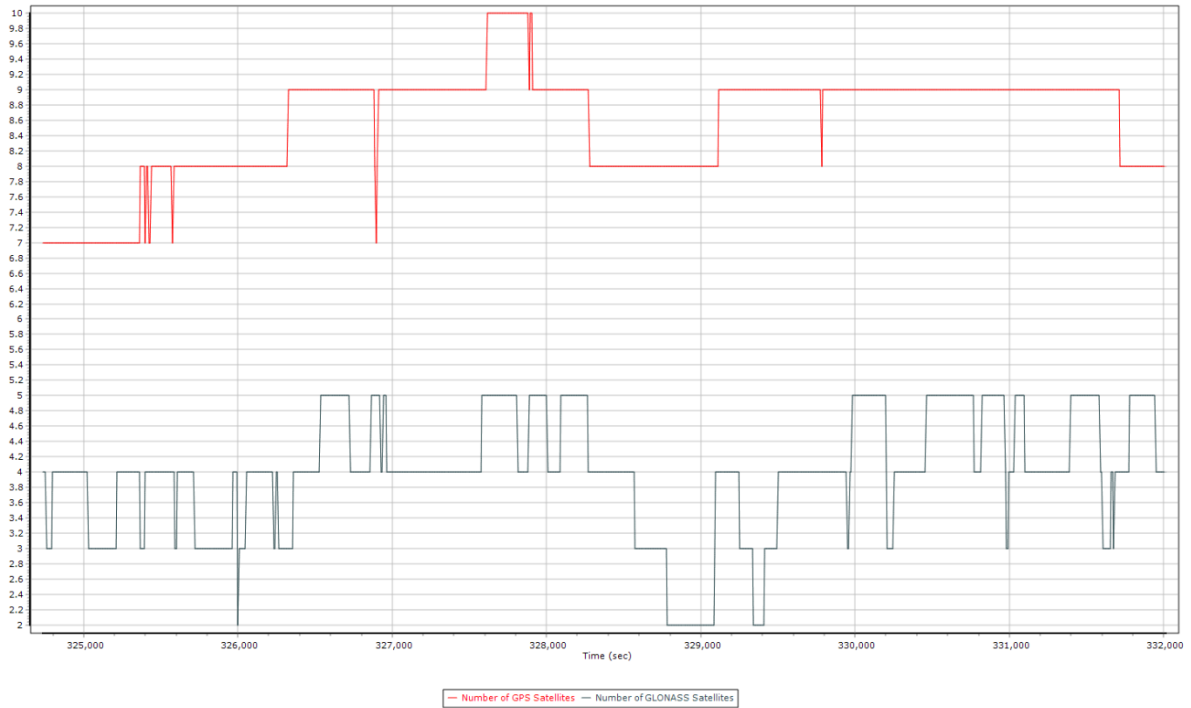
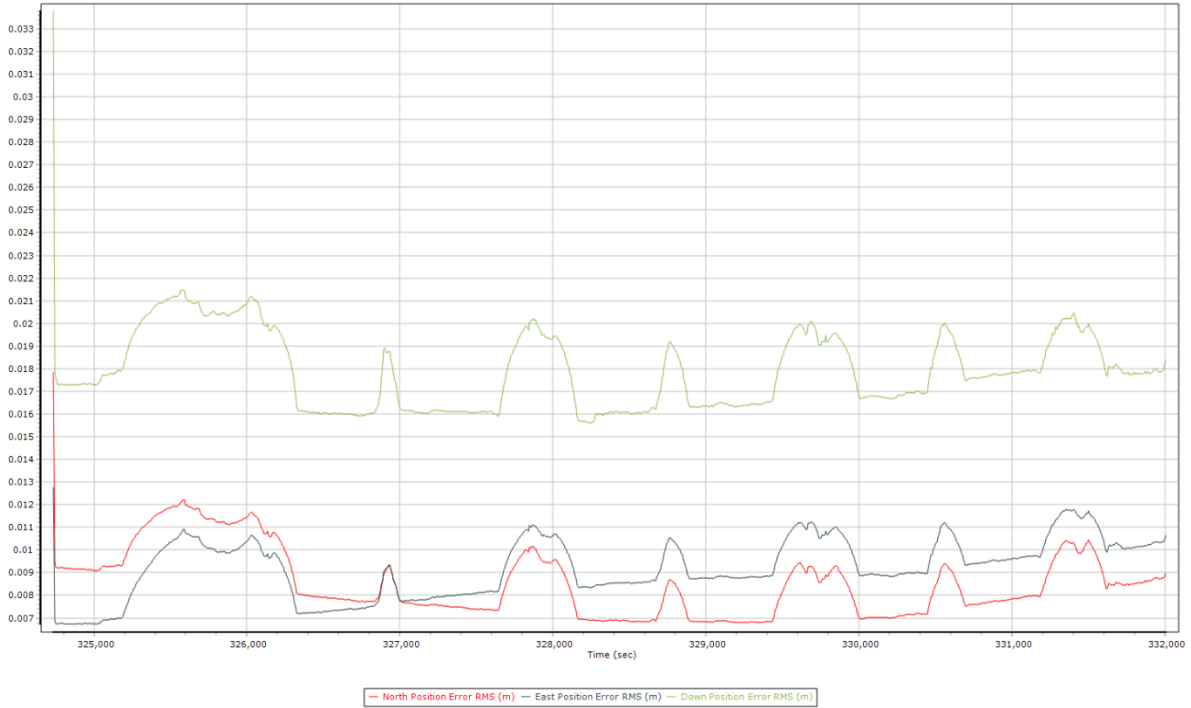
Z:

Standard Deviation

<3cm 10cm 50cm 1m 10m

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





Project Settings [X]

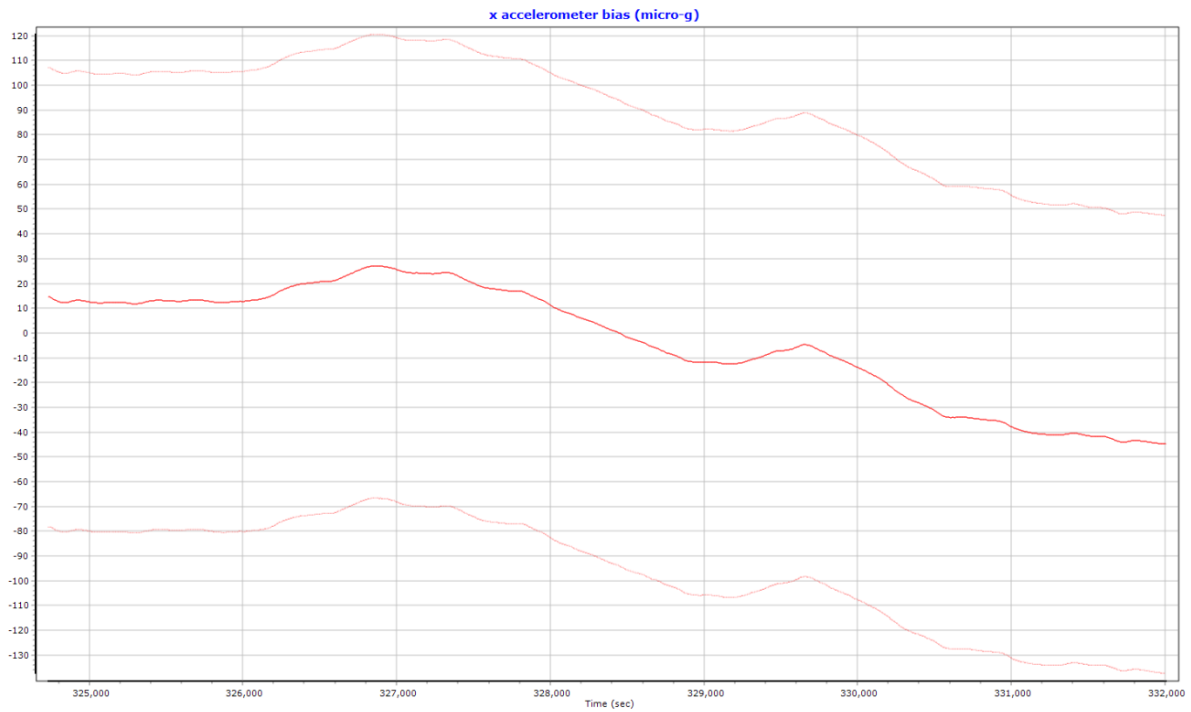
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing**
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

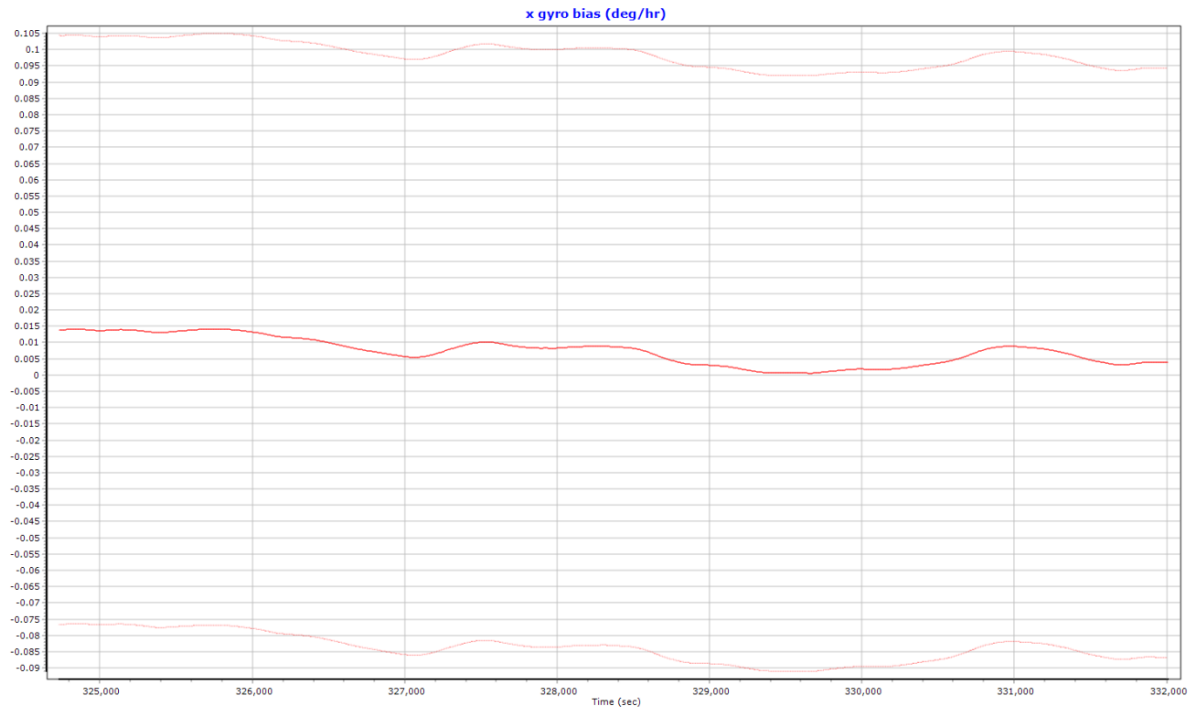
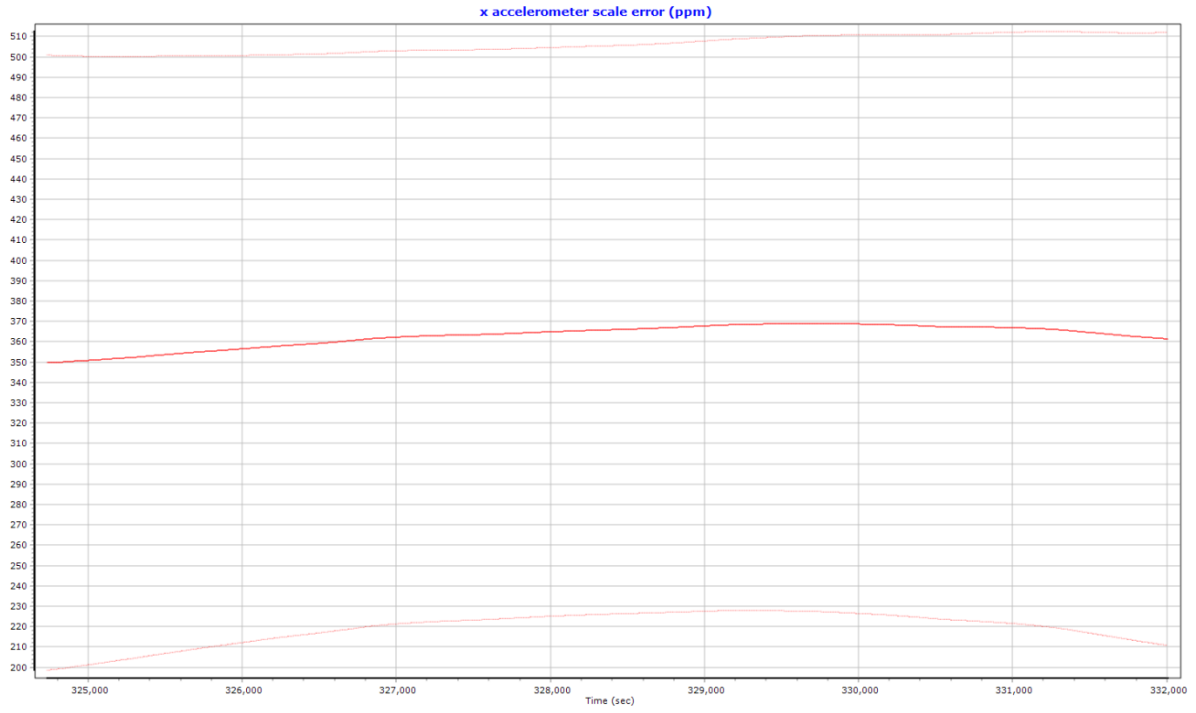
Timing

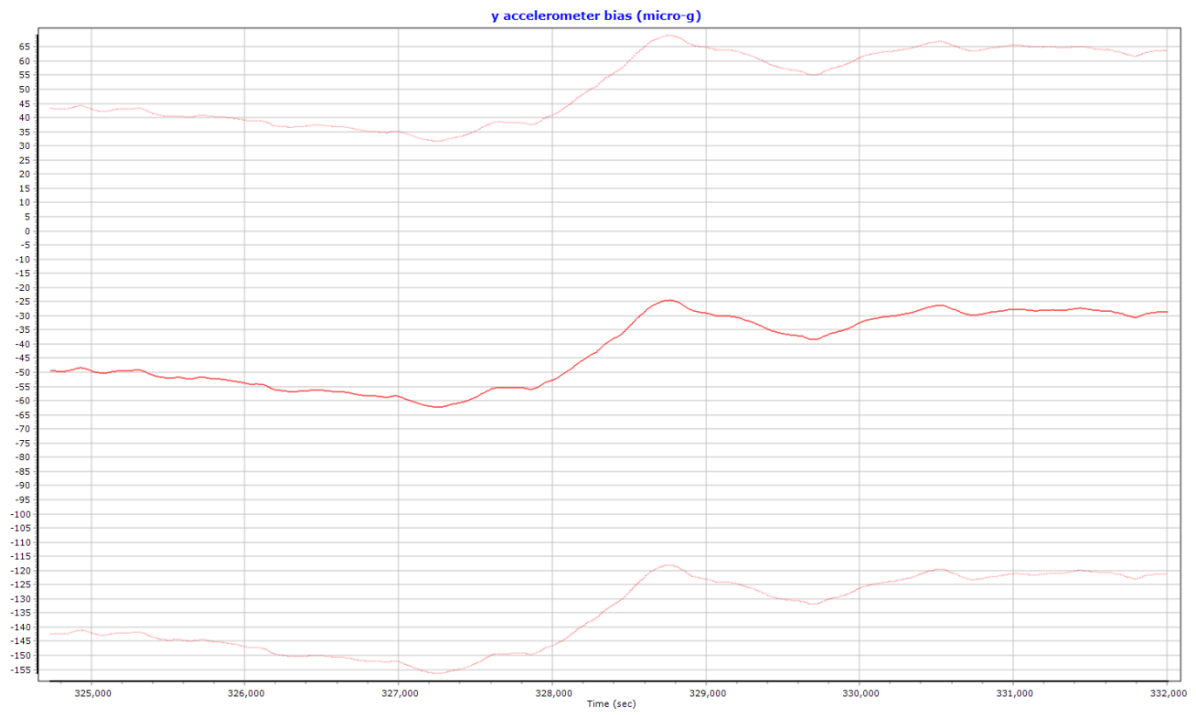
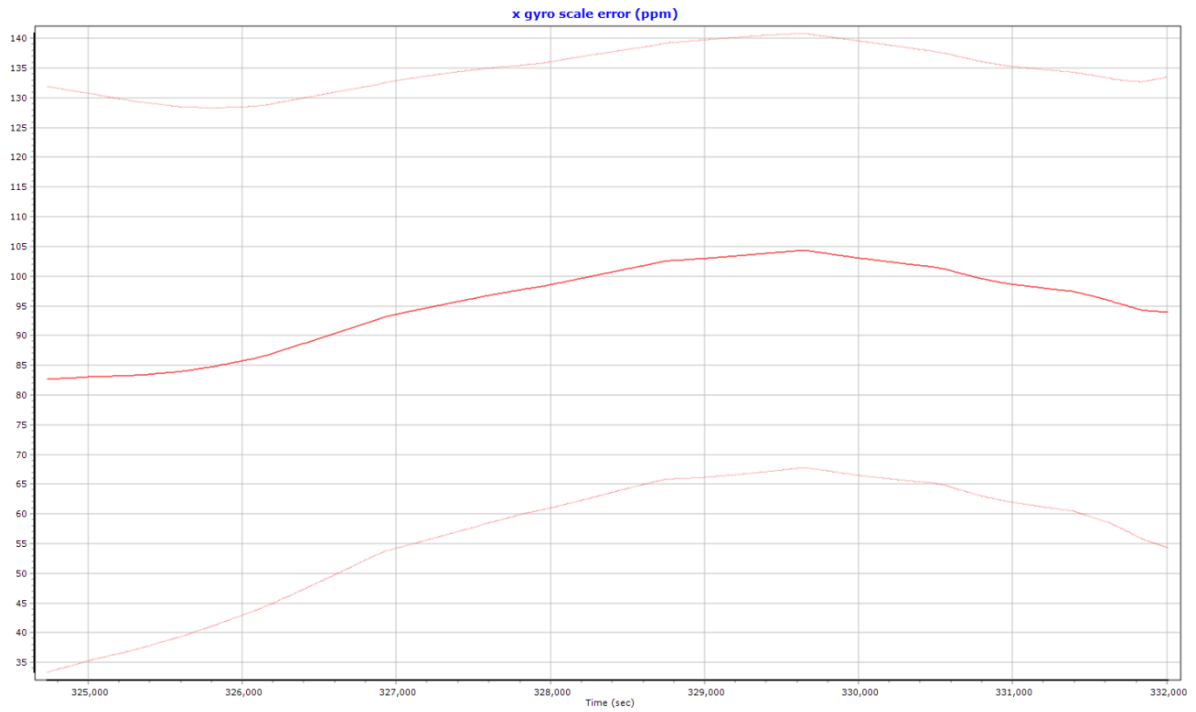
Start: 324732.349
End: 332018.034
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

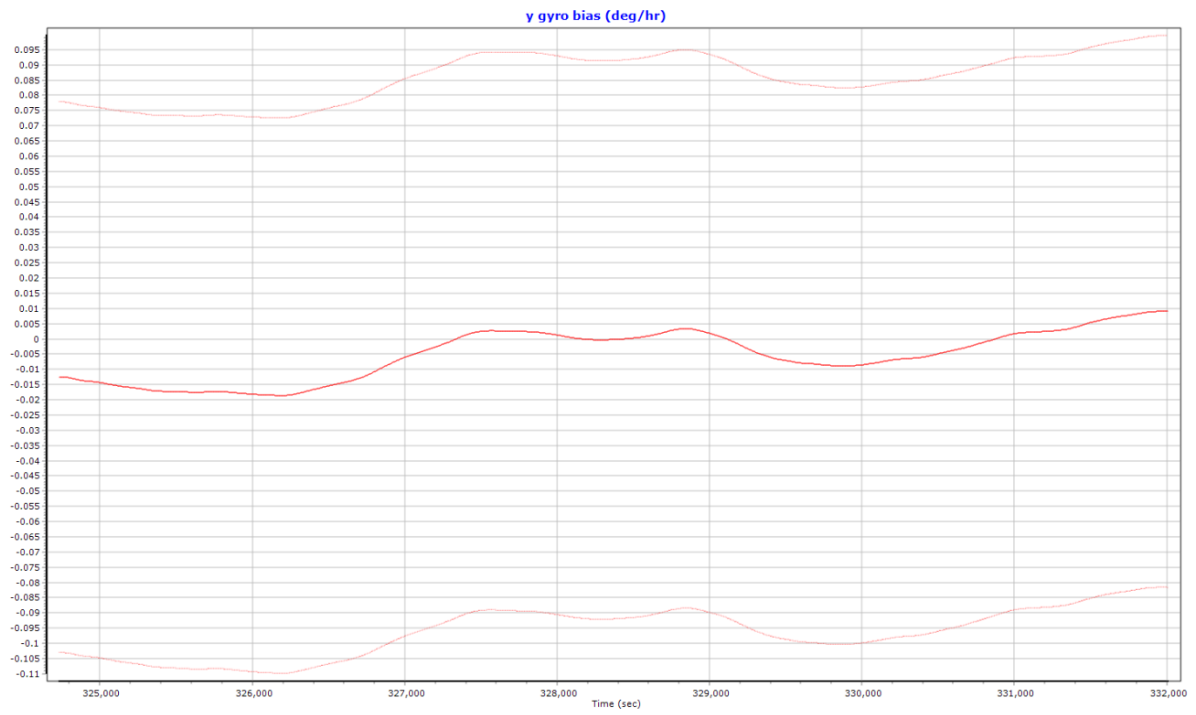
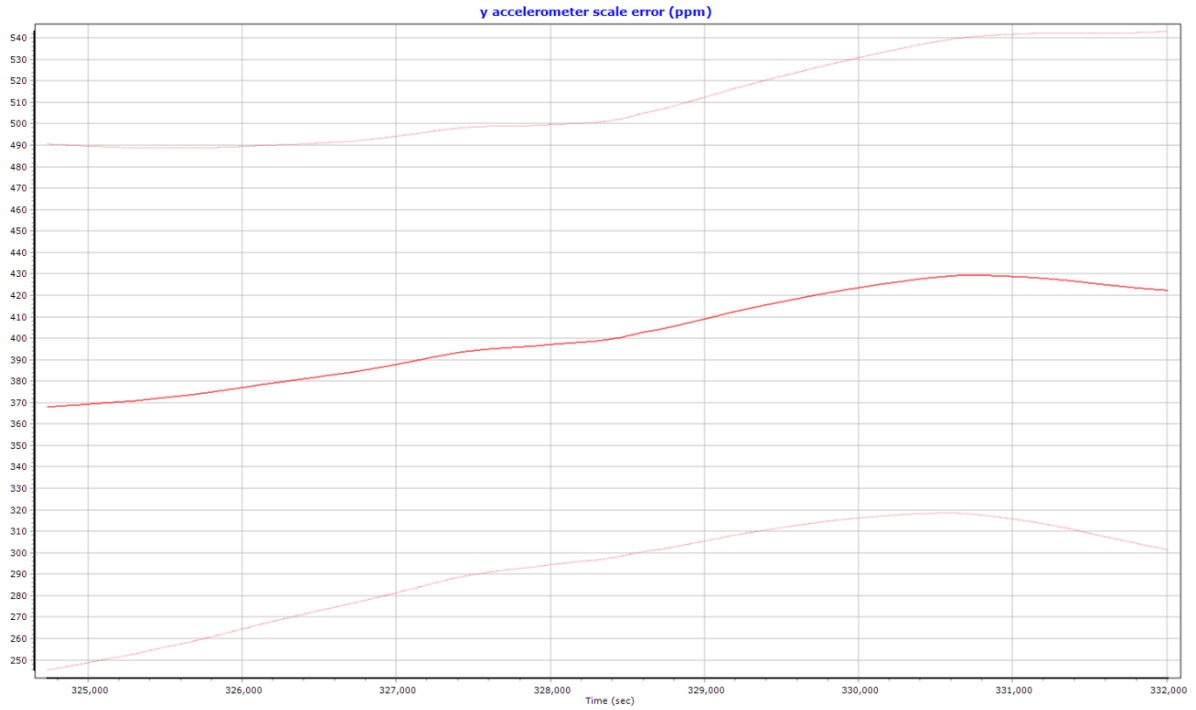
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

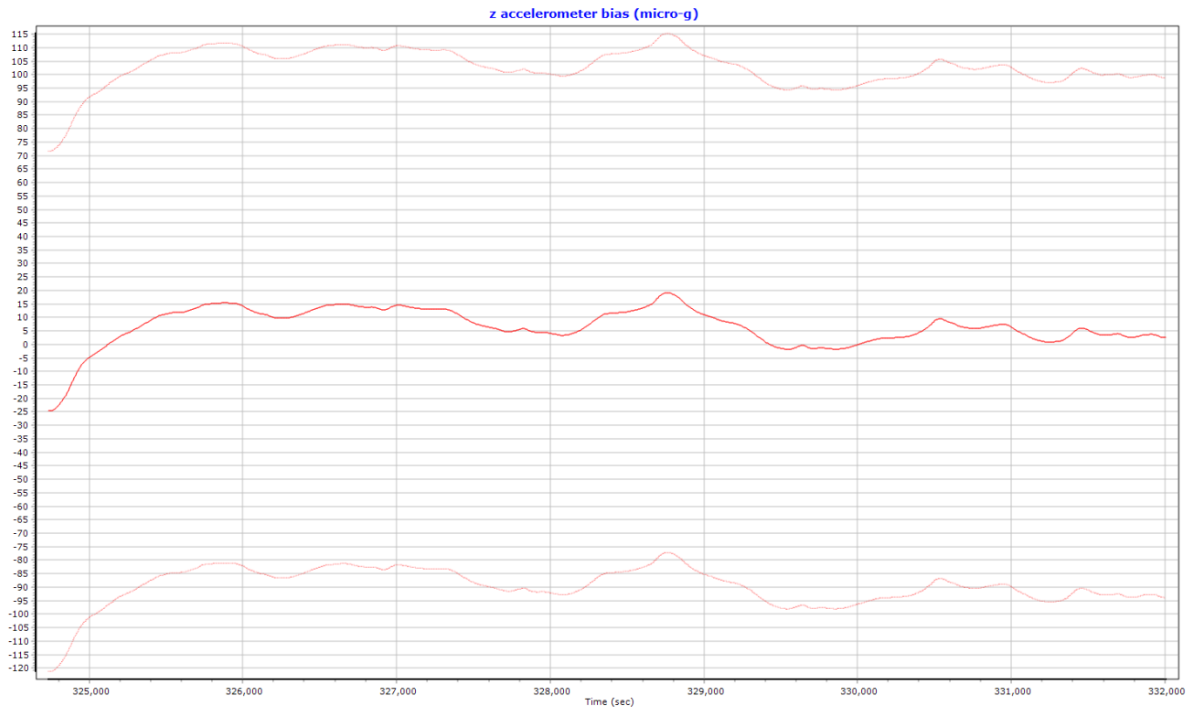
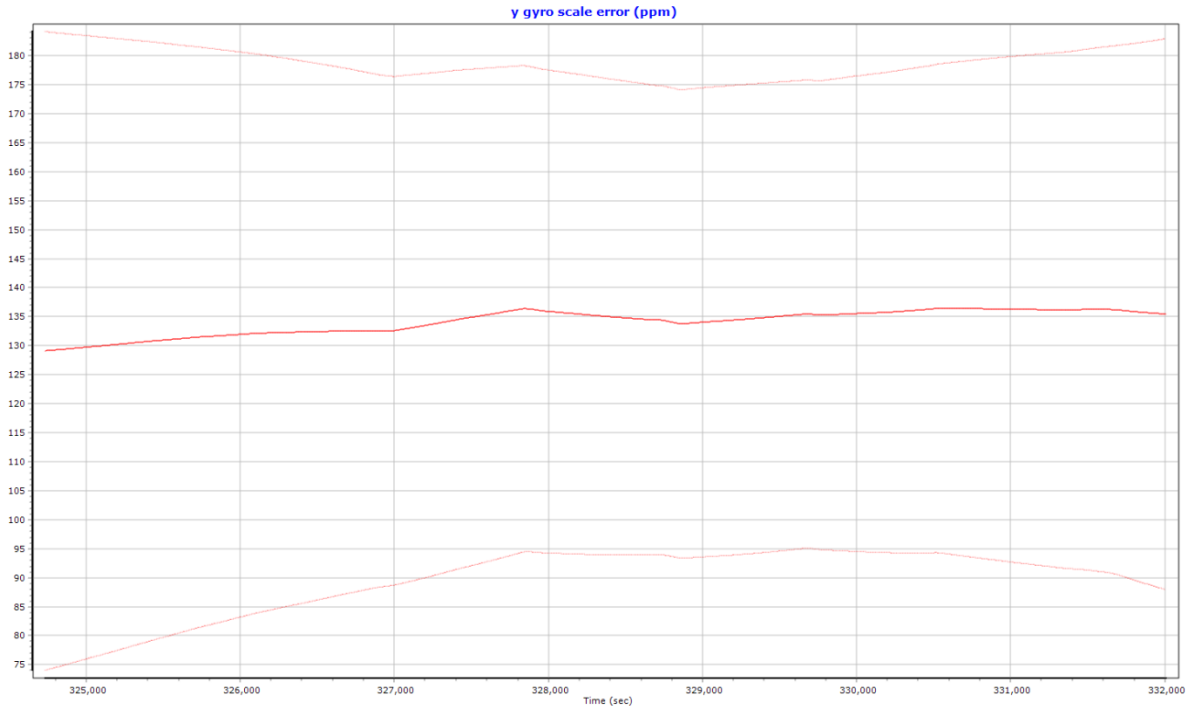
OK Cancel

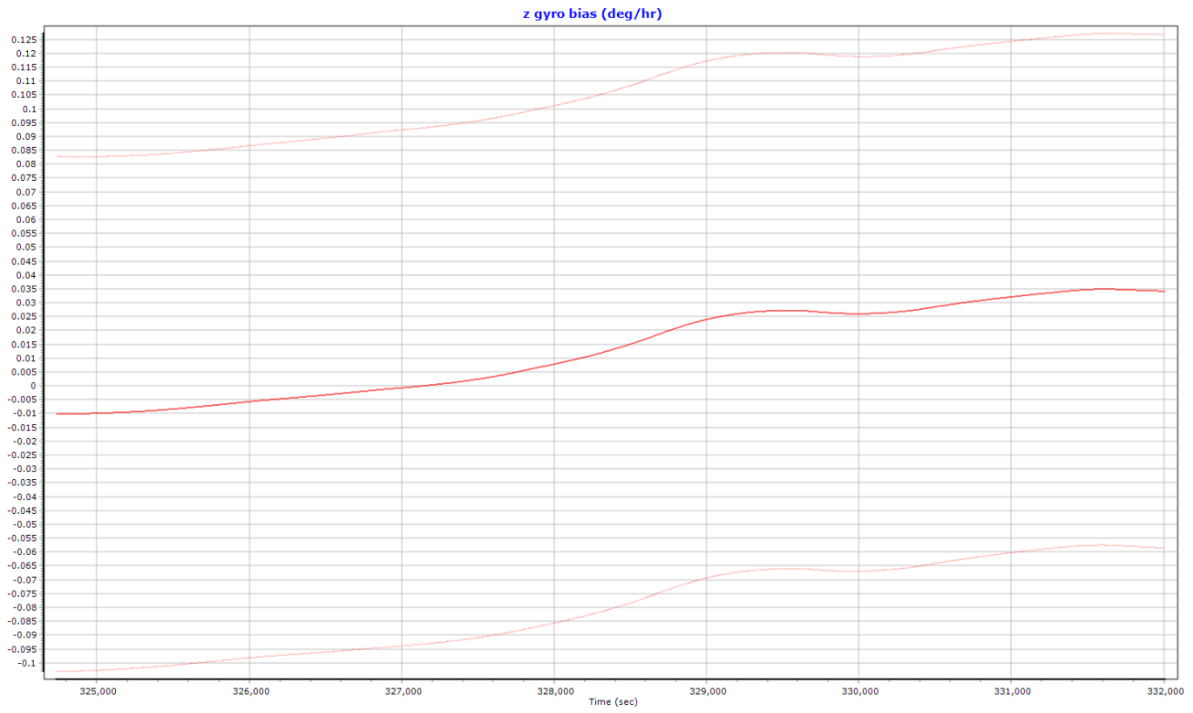
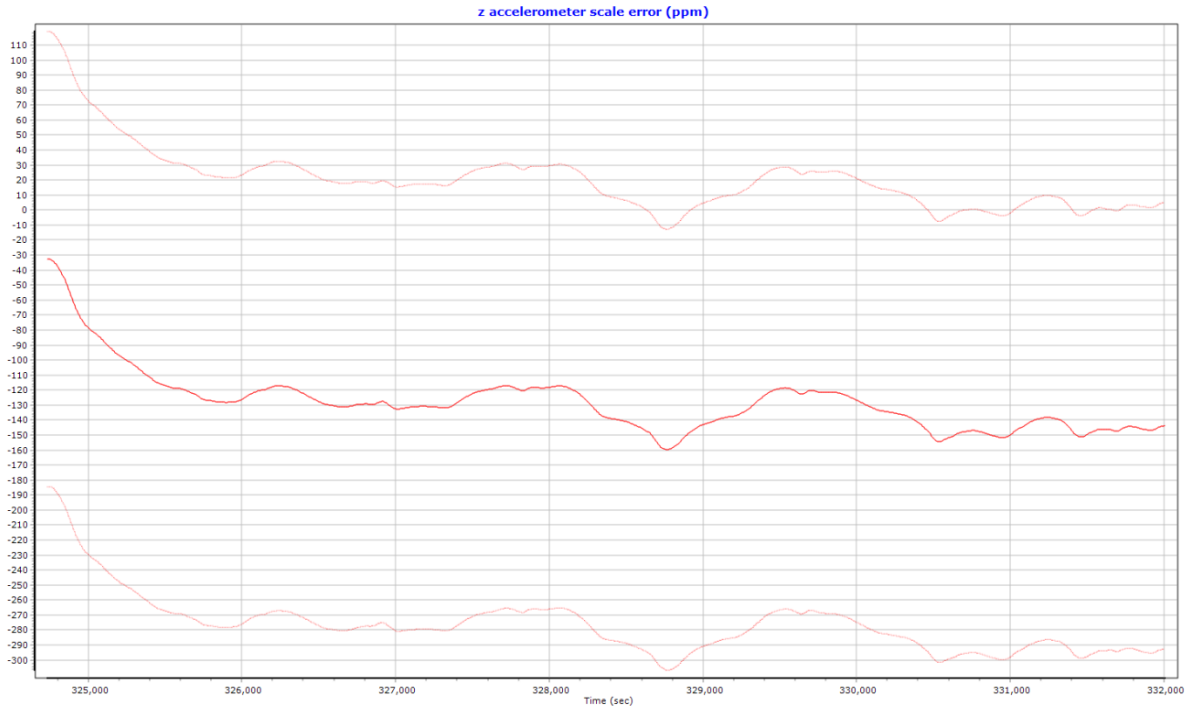


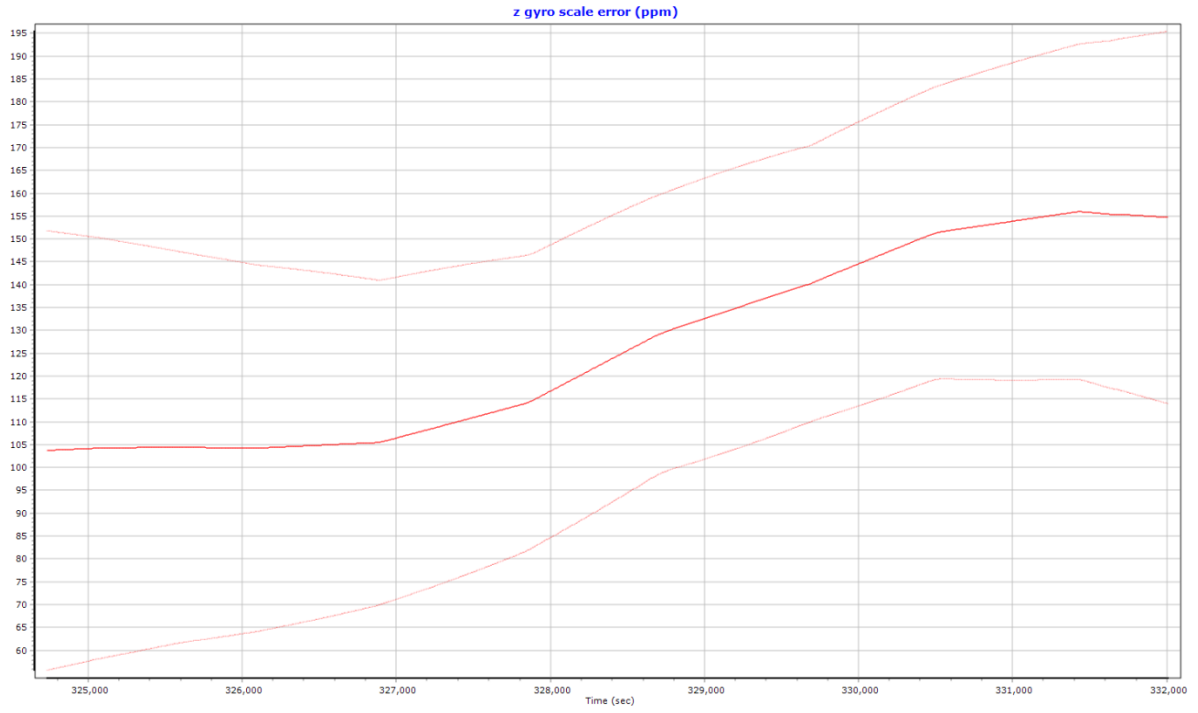




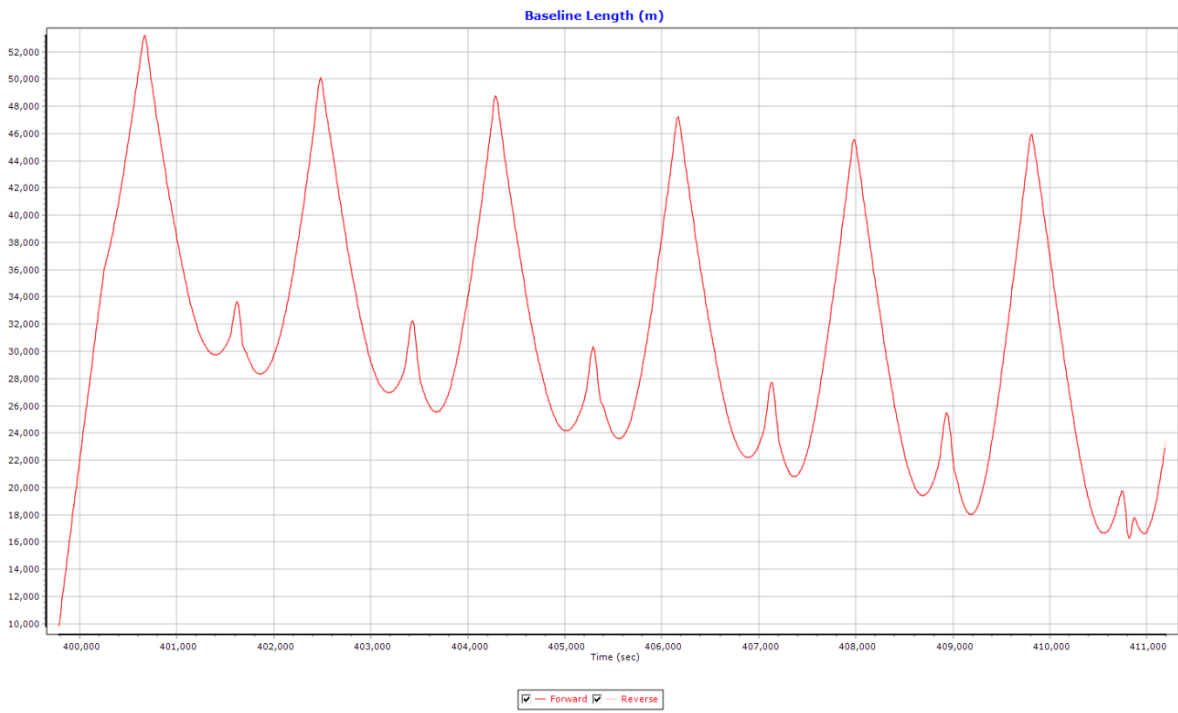
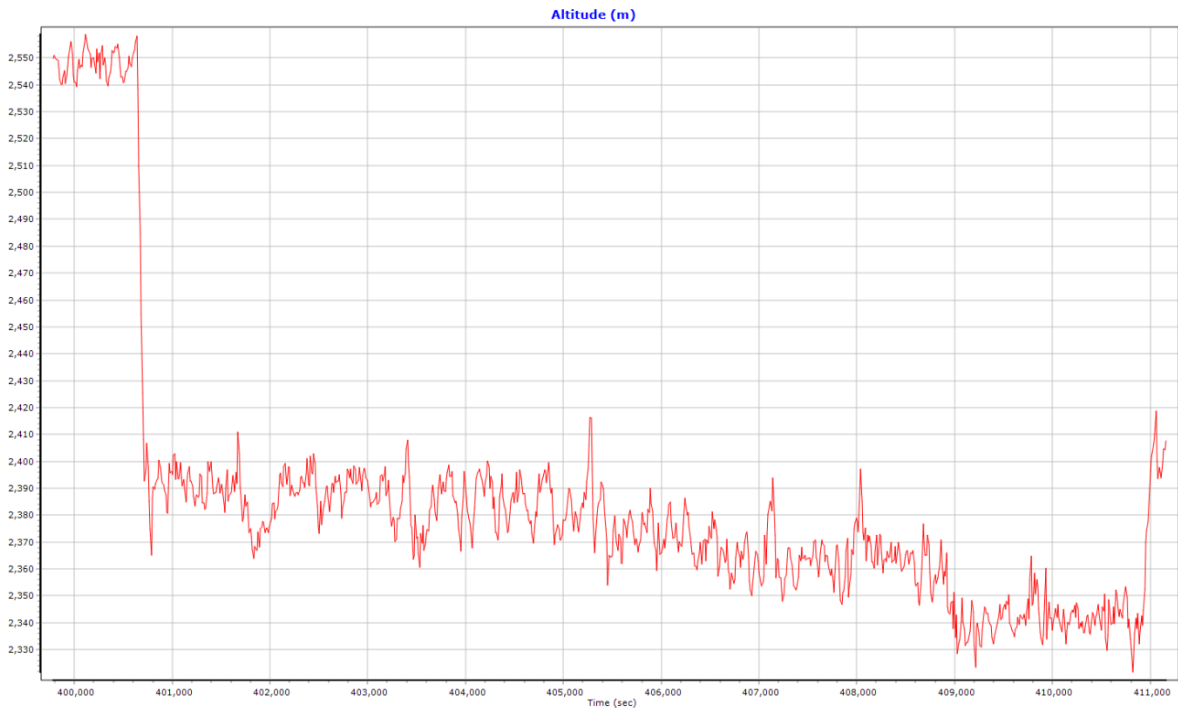


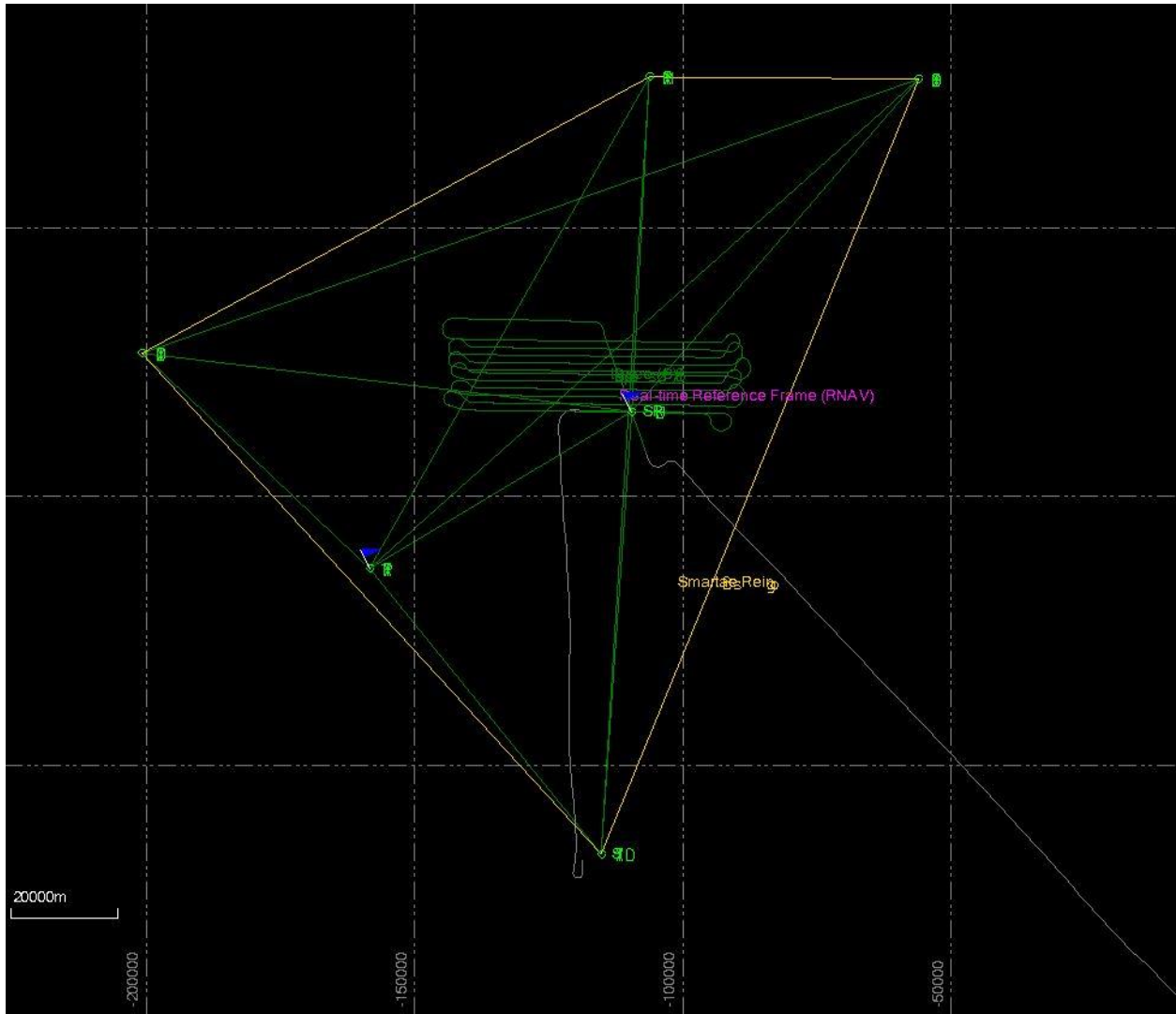






RBV18060A







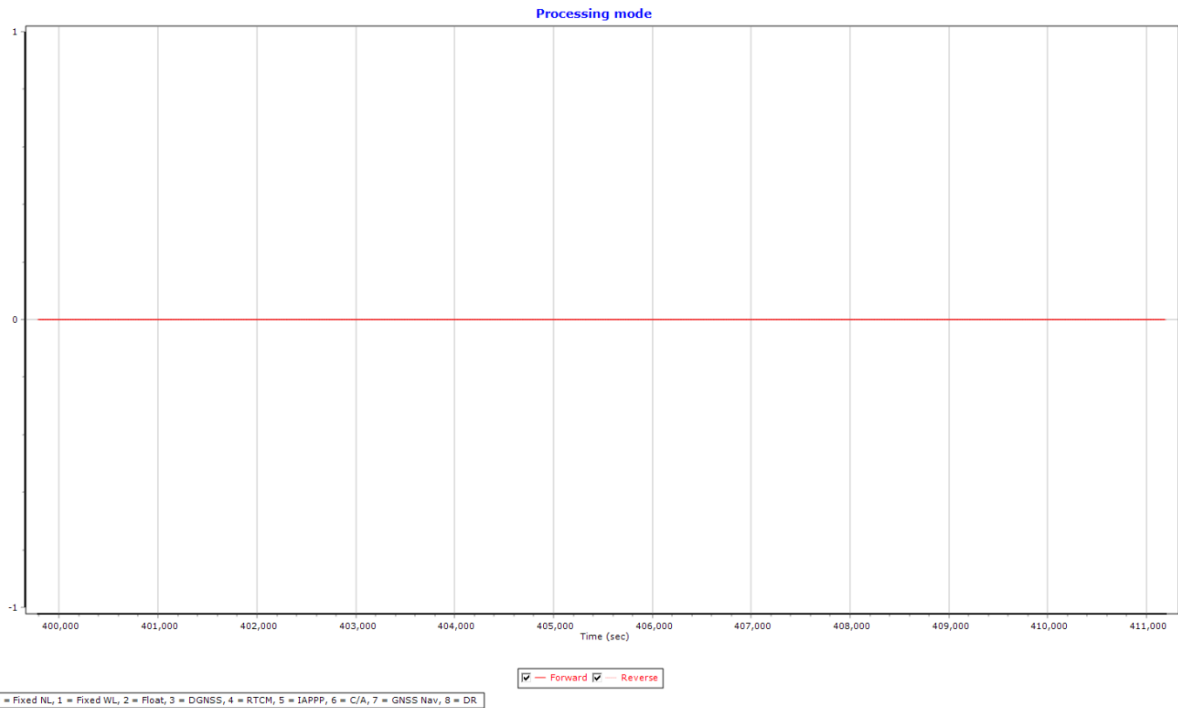
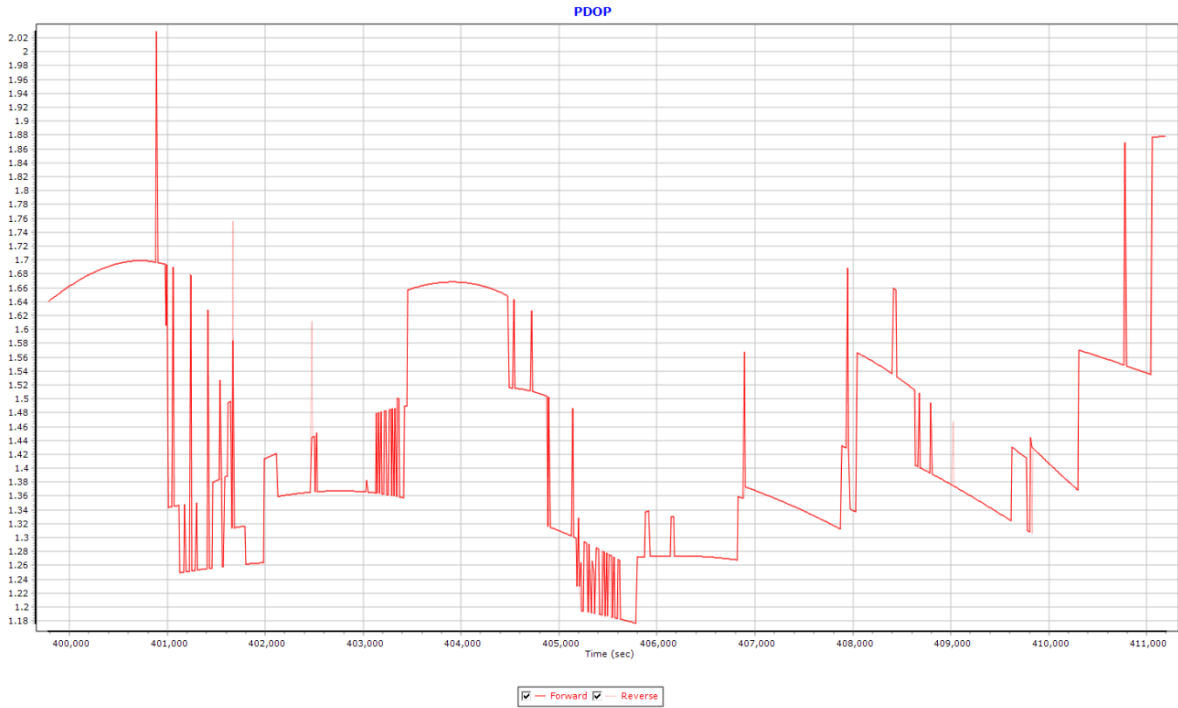
Project Settings

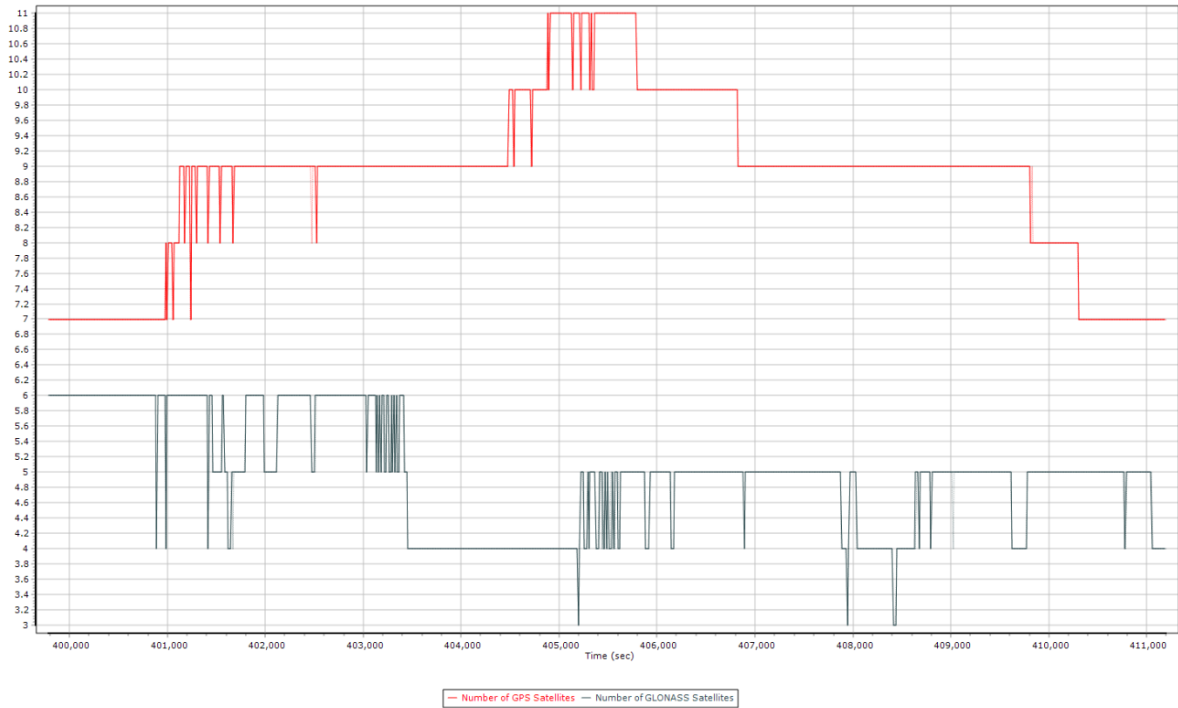
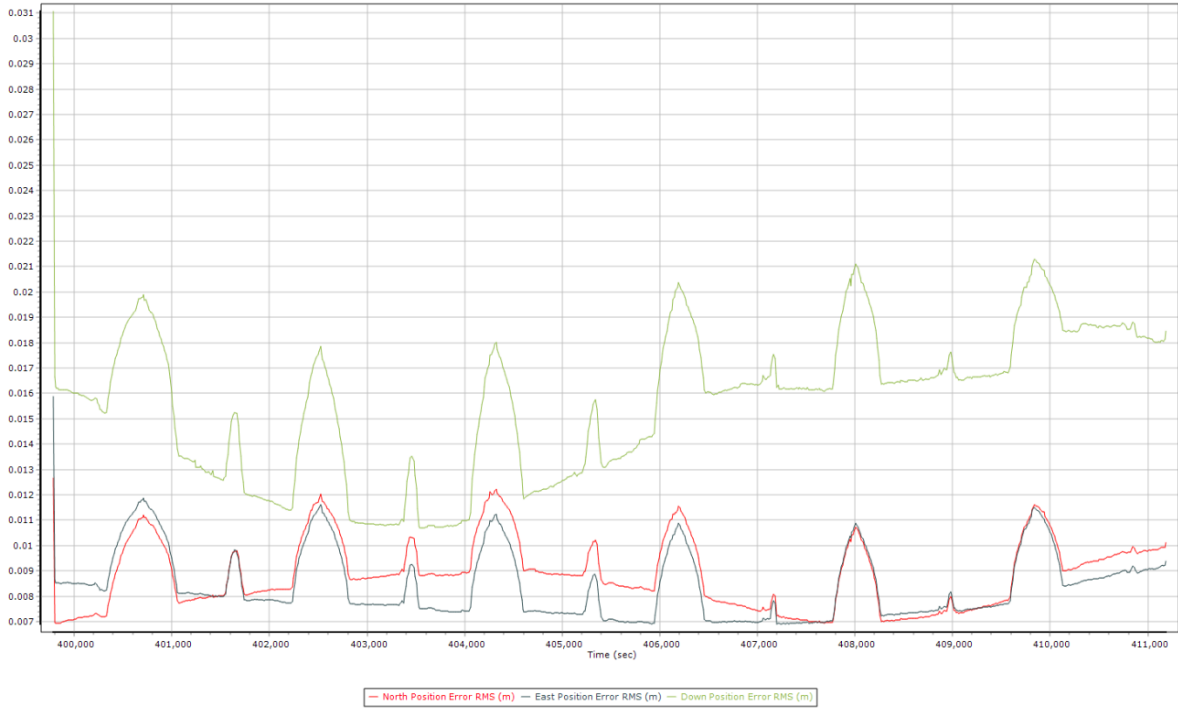
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

Stabilized Mount to IMU Lever Arm		Stabilized Mount to IMU Mounting Angles	
X	<input type="text" value="0.000 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"/>
Stabilized Mount to Primary GNSS Lever Arm		Aircraft to Stabilized Mount Mounting Angles	
X	<input type="text" value="-0.031 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="0.004 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.611 m"/>	Z	<input type="text" value="0.000 deg"/>
Standard Deviation			
<input checked="" 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.

OK Cancel





Project Settings

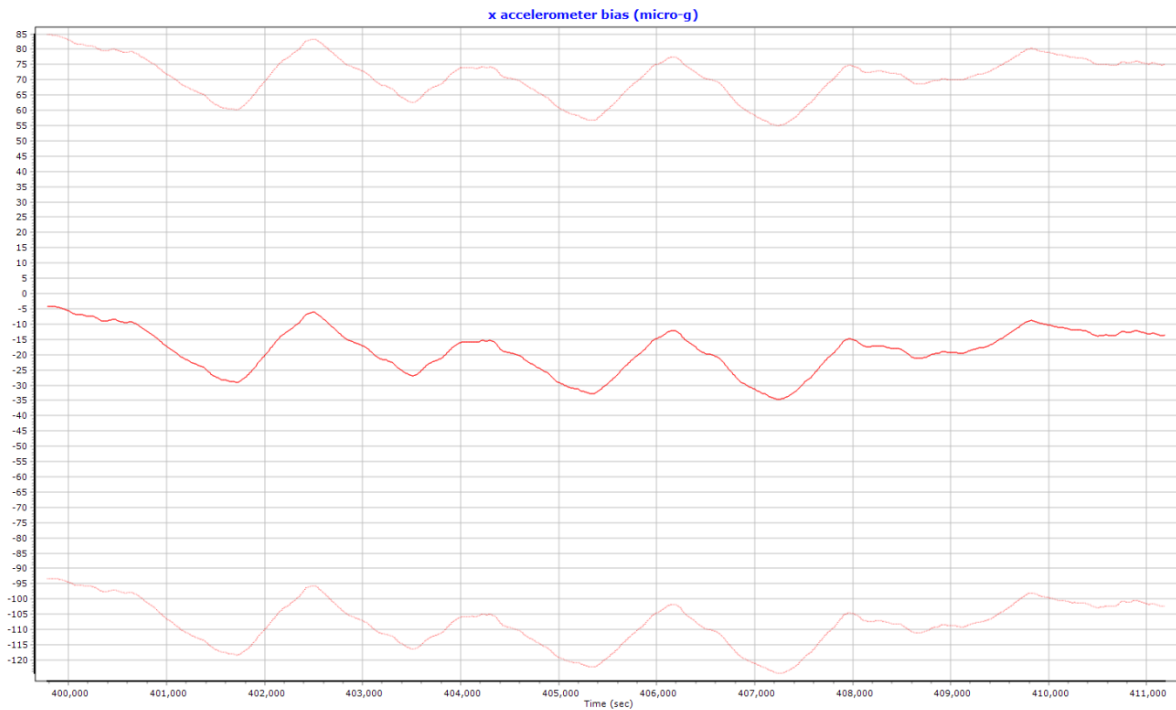
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

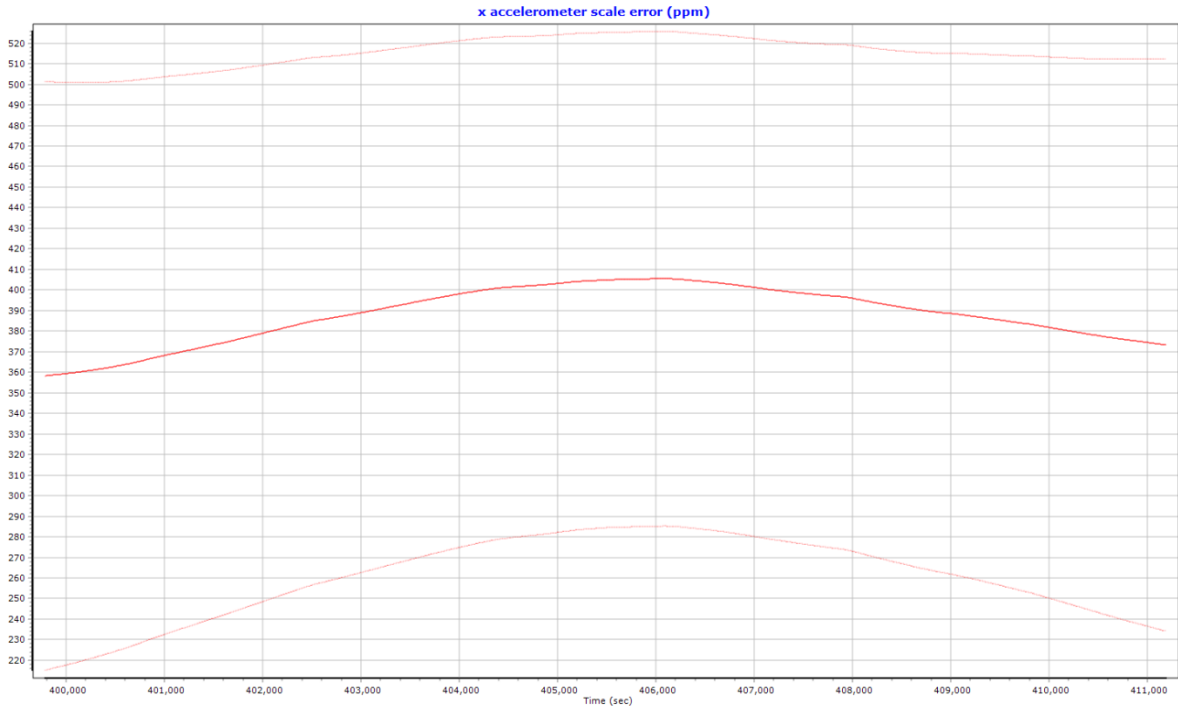
Timing

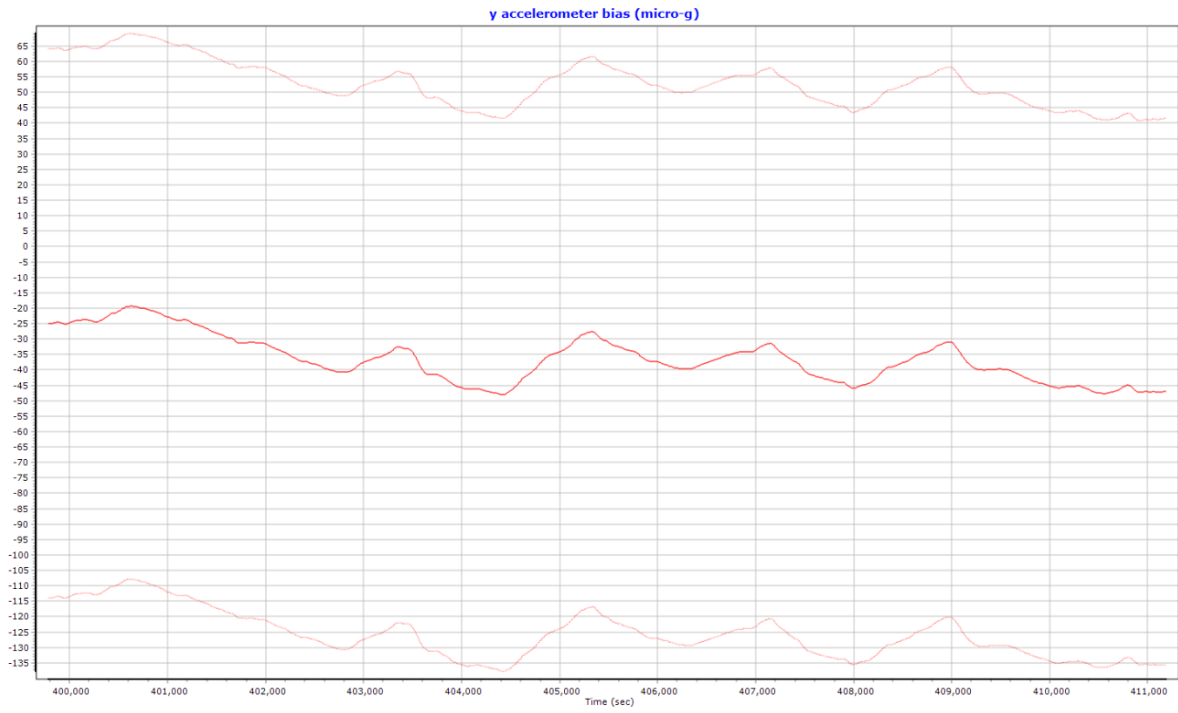
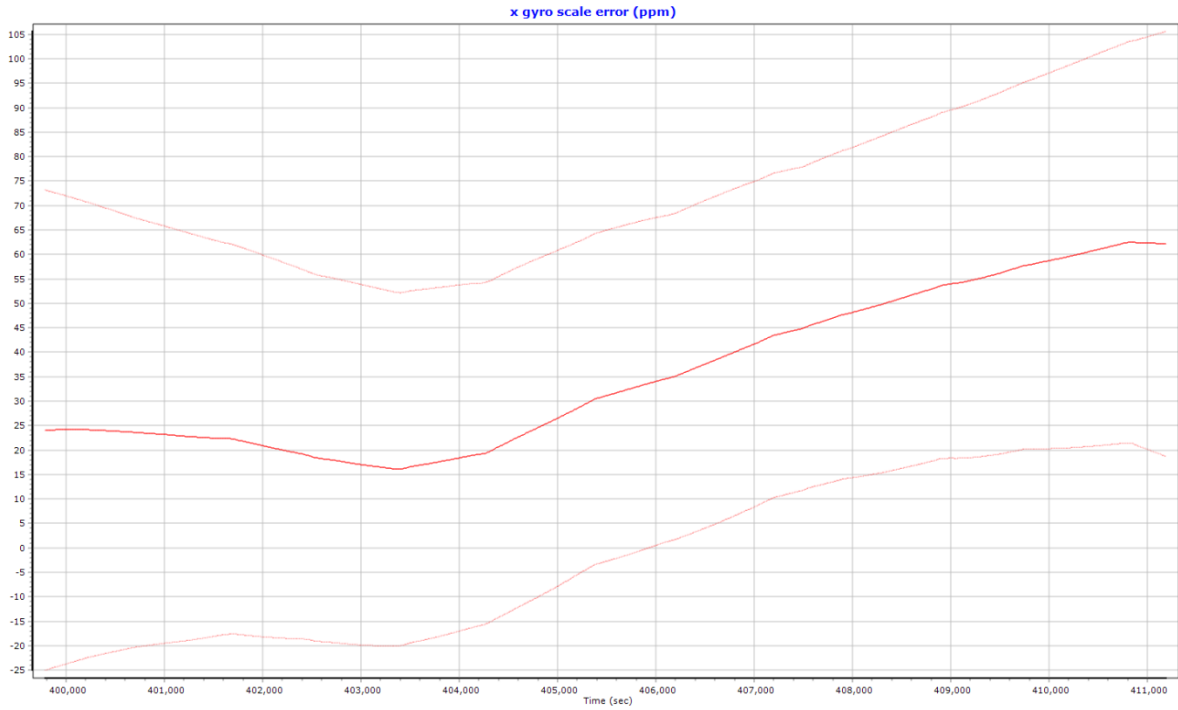
Start: 399782.330
End: 411198.968
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

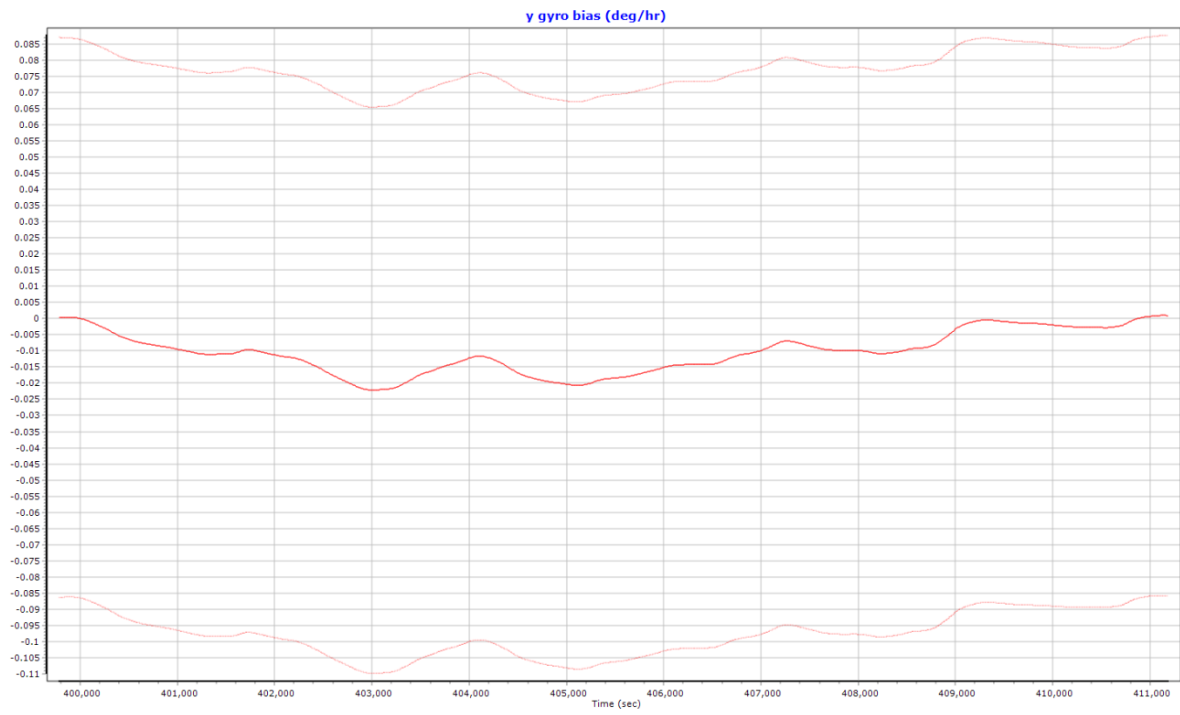
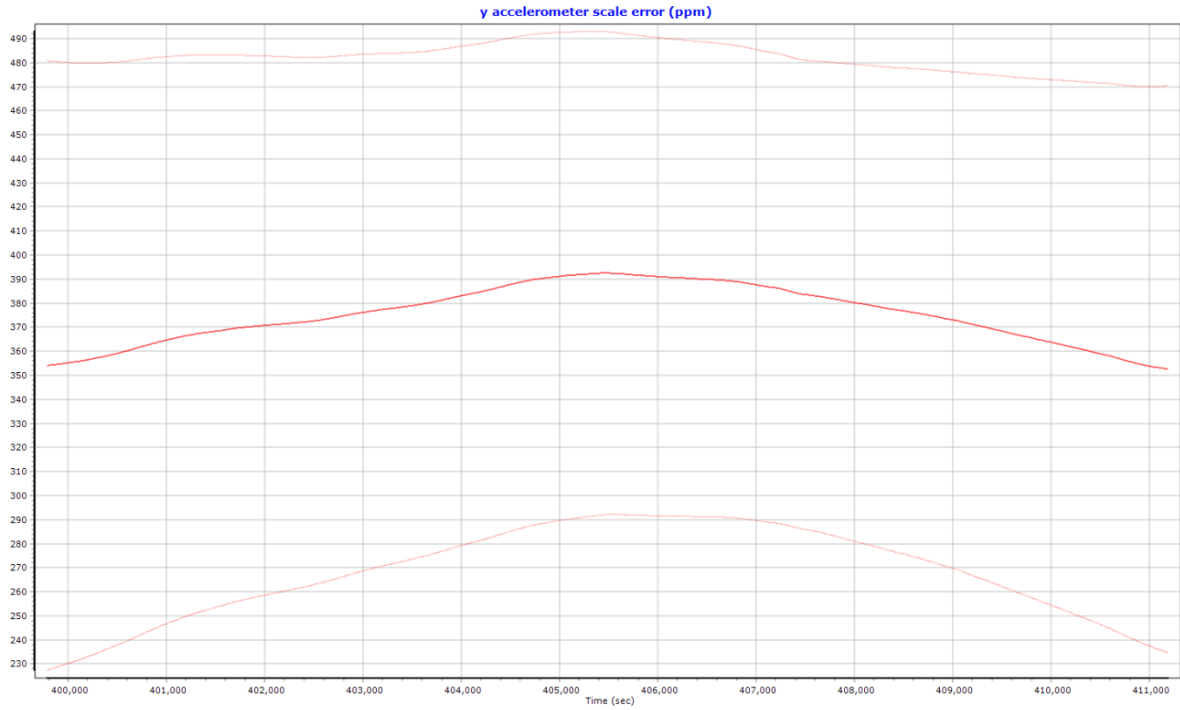
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

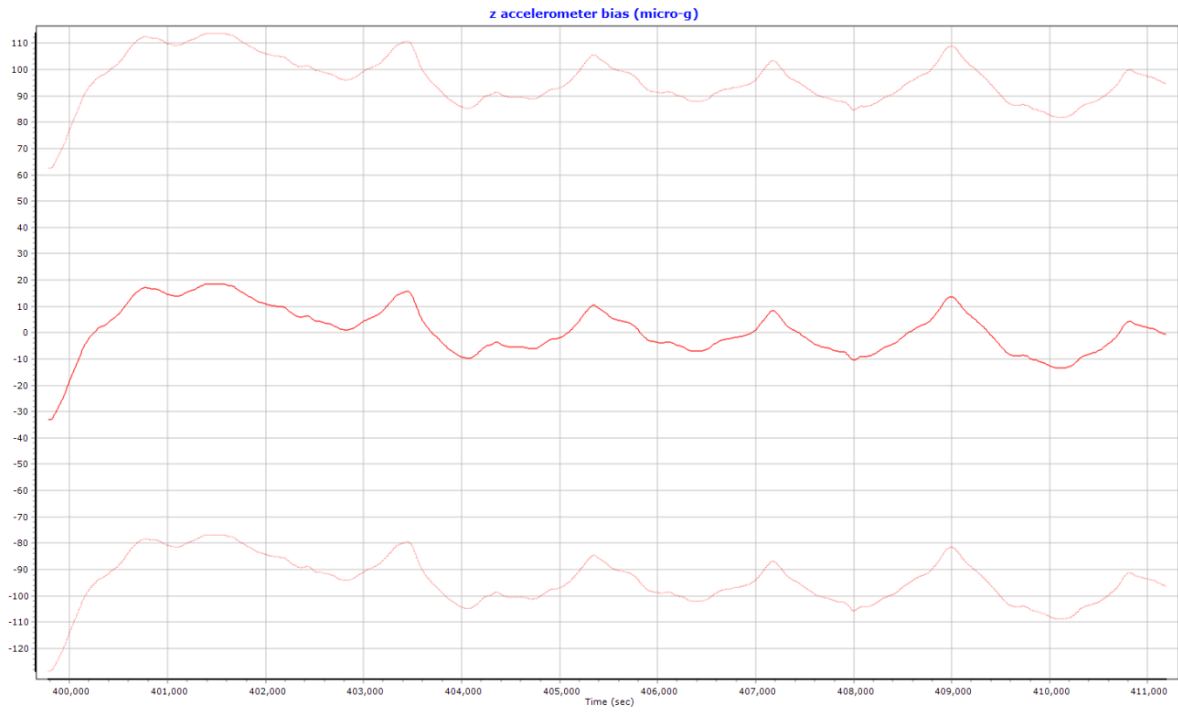
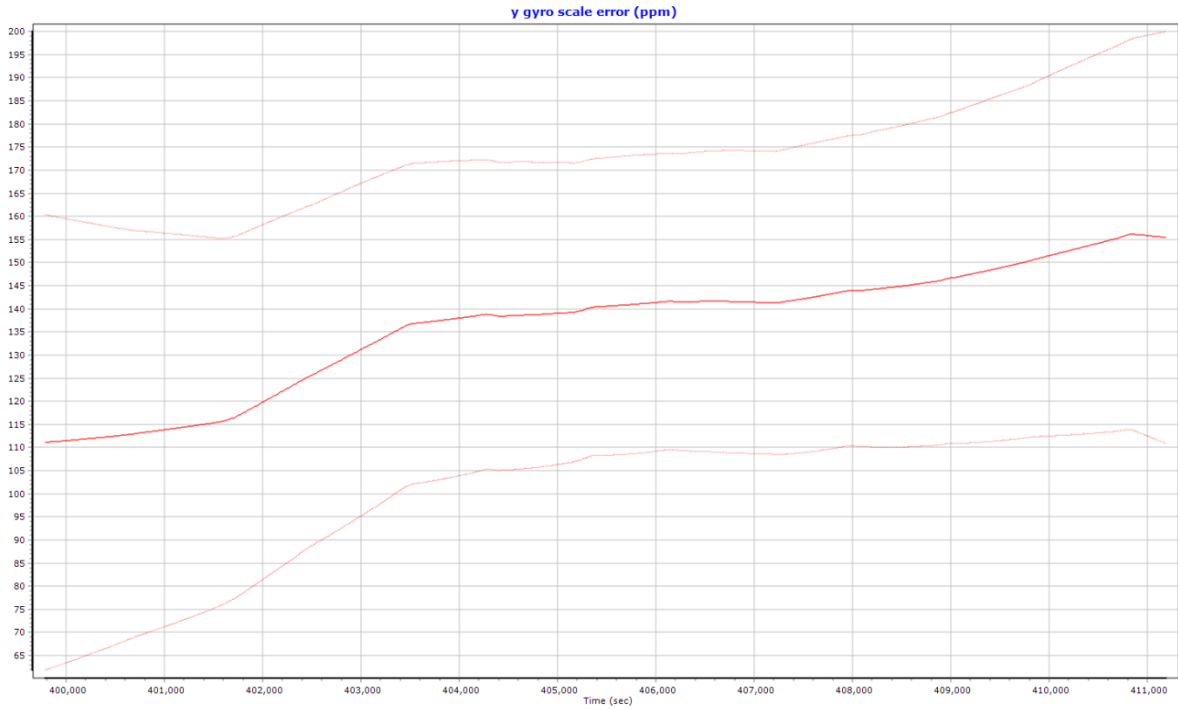
OK Cancel

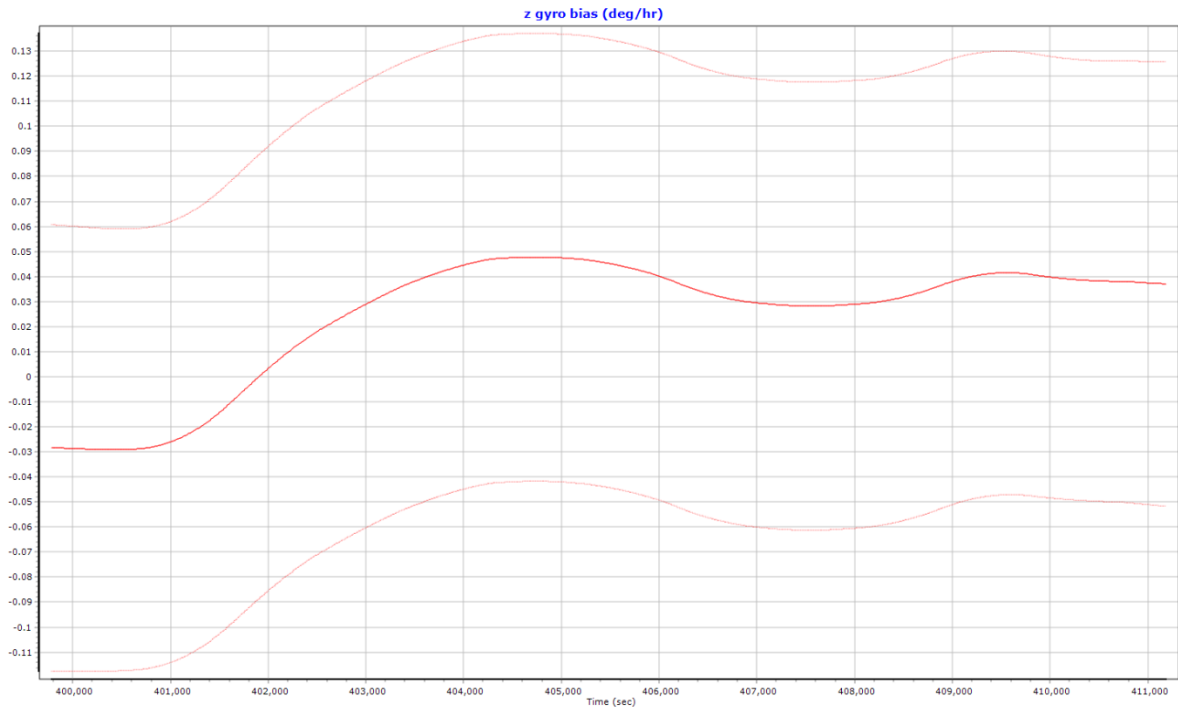


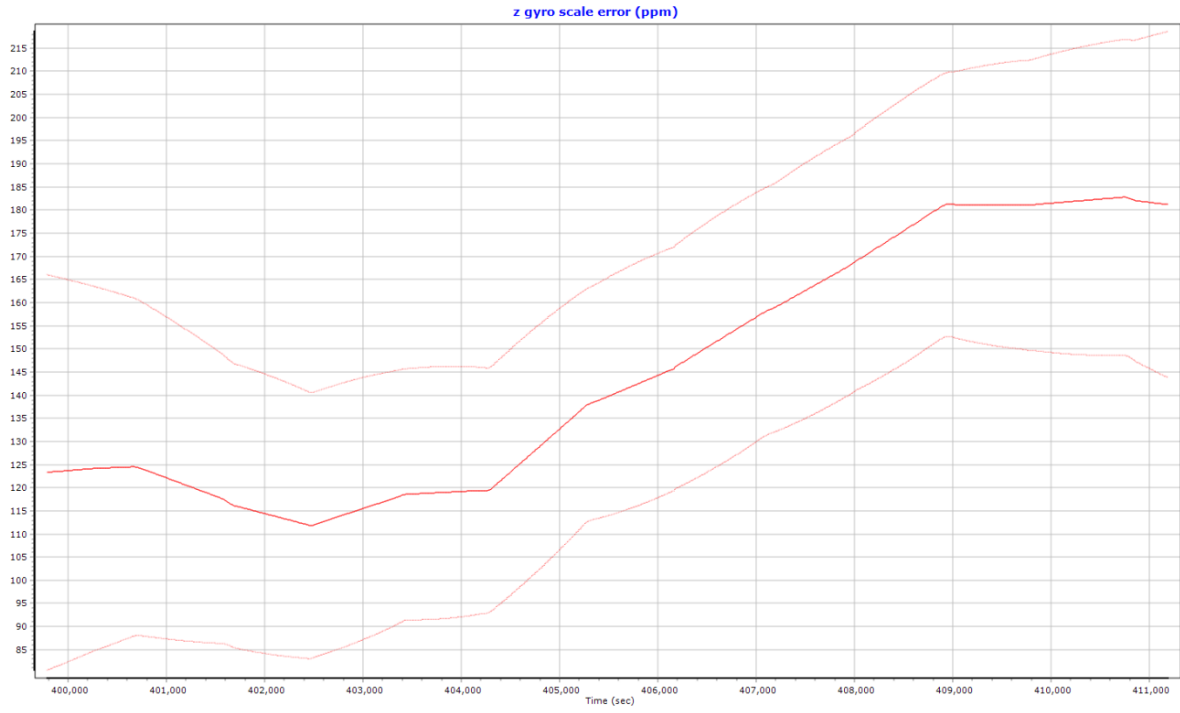




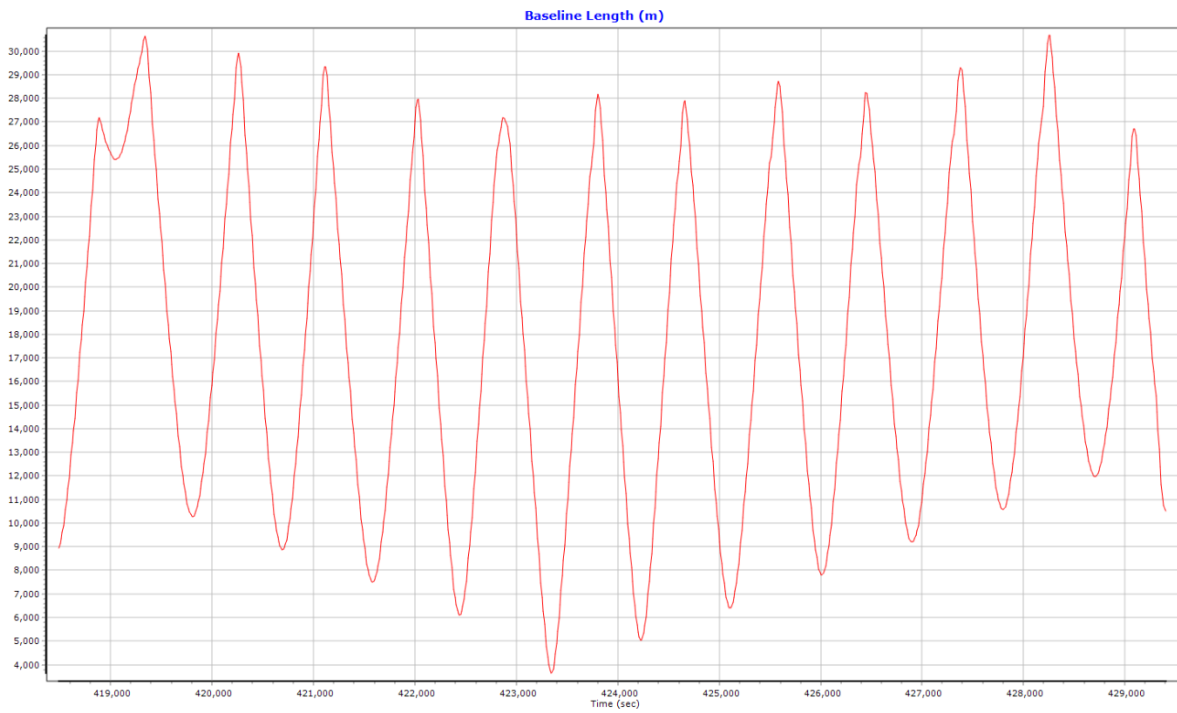
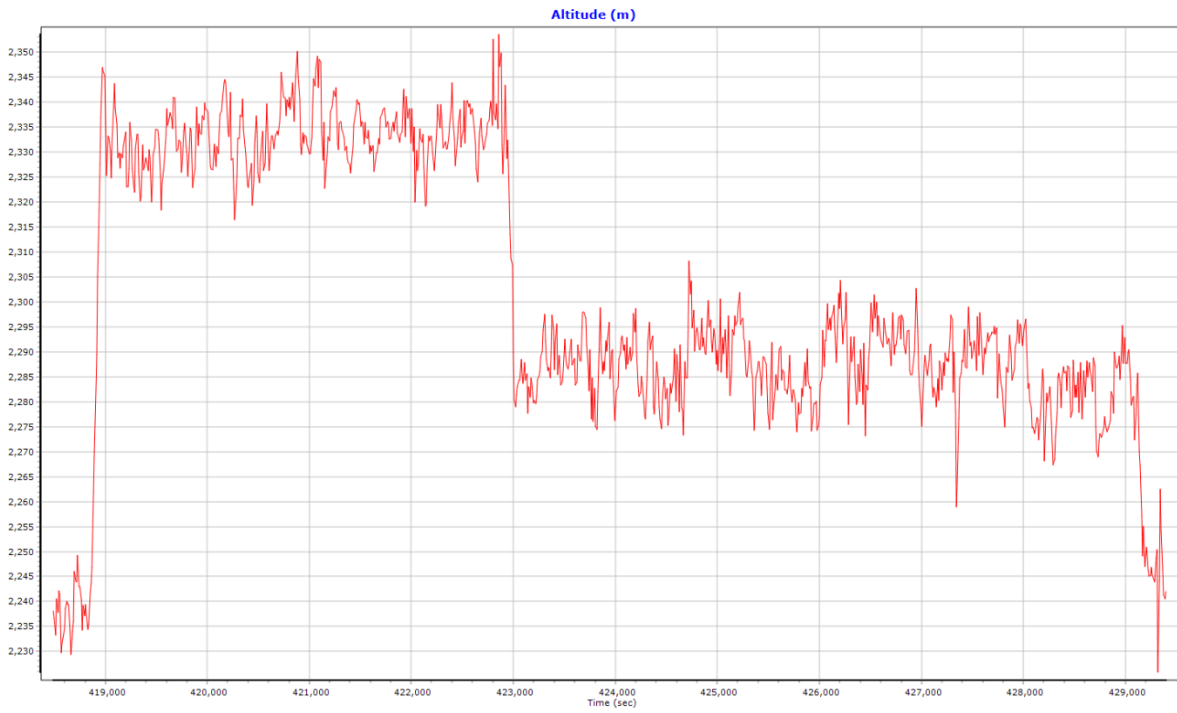


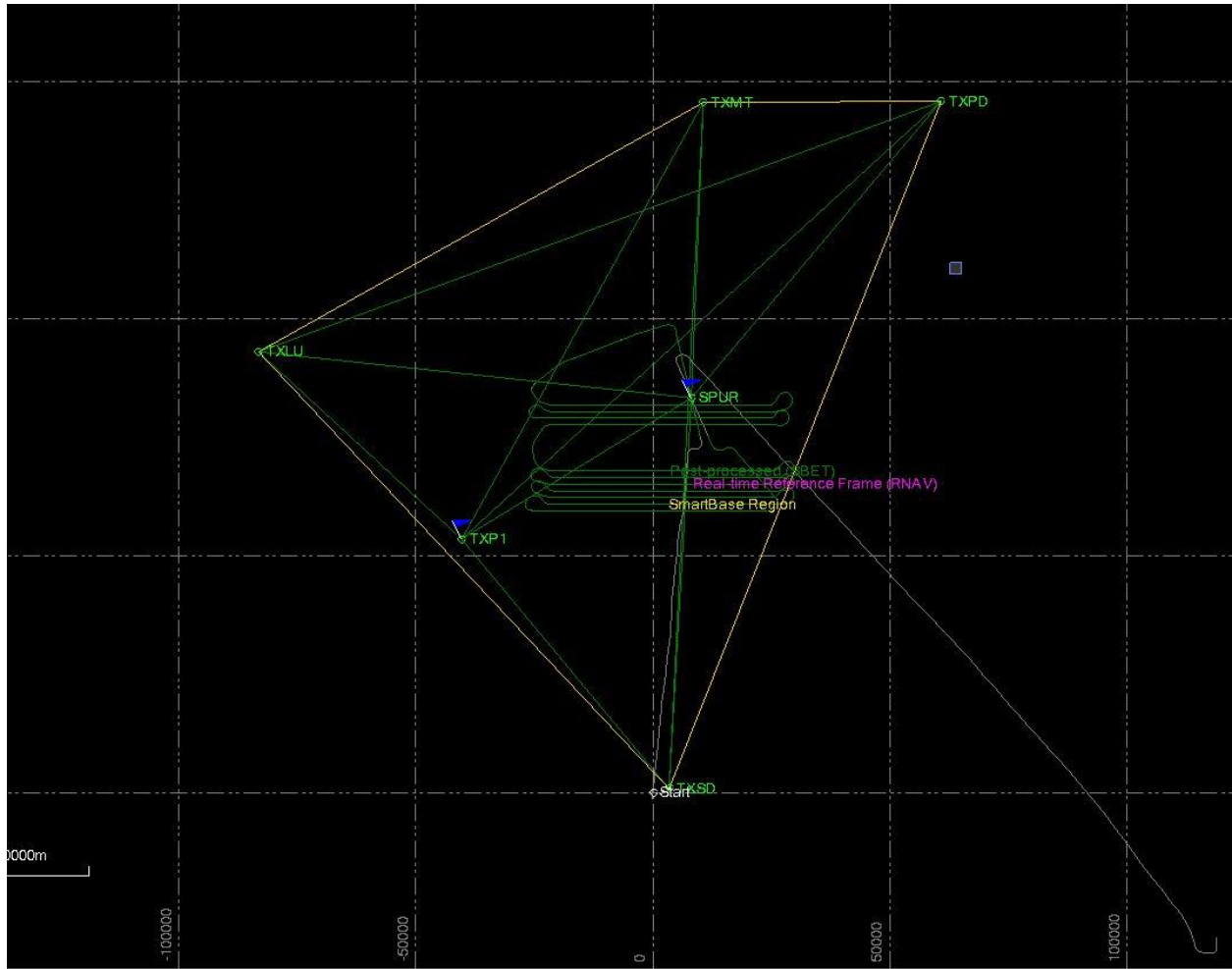


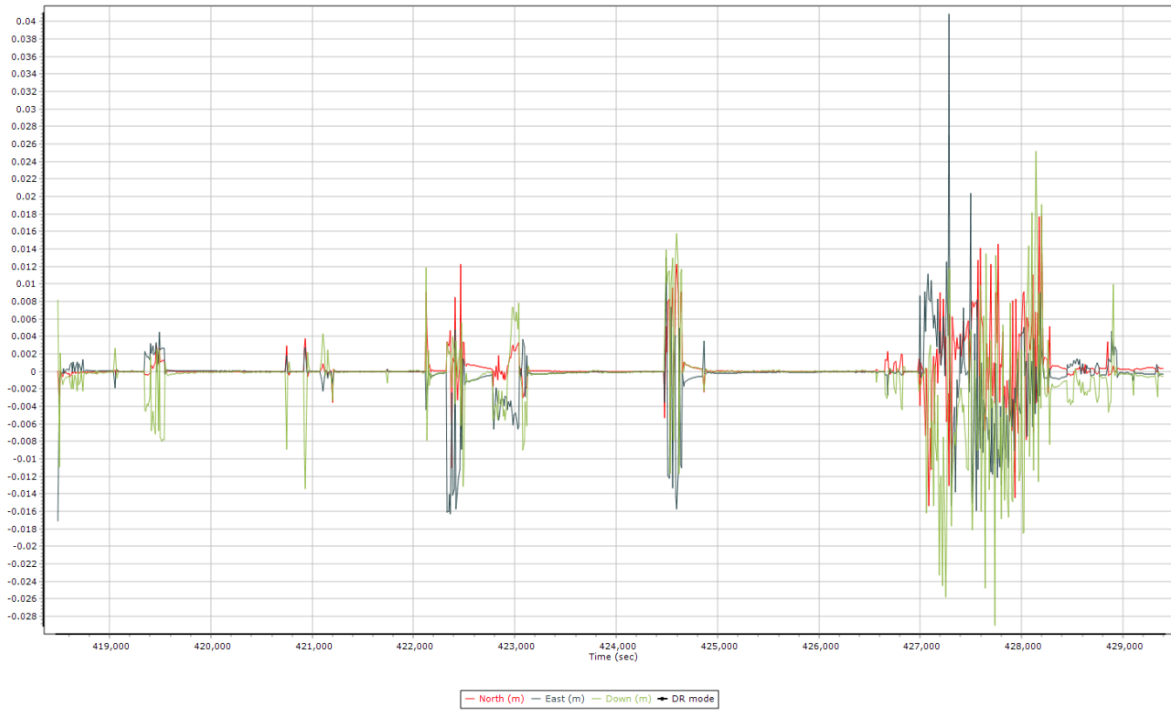




RBV18060B







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:

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

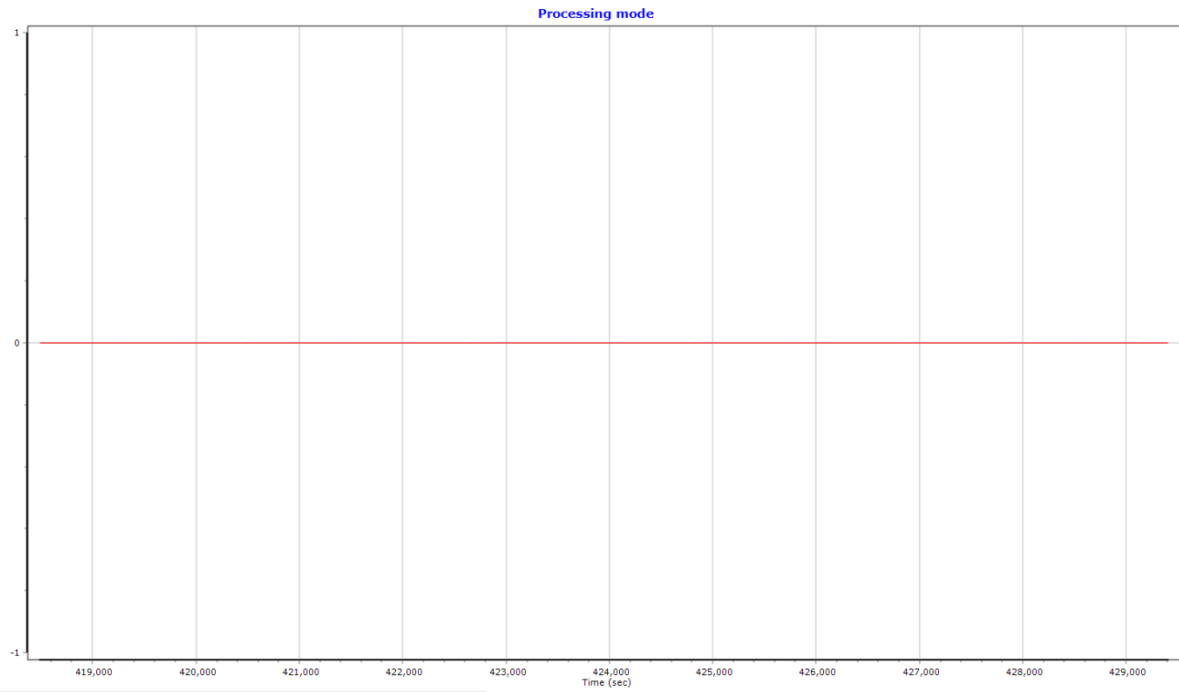
Aircraft to Stabilized Mount Mounting Angles

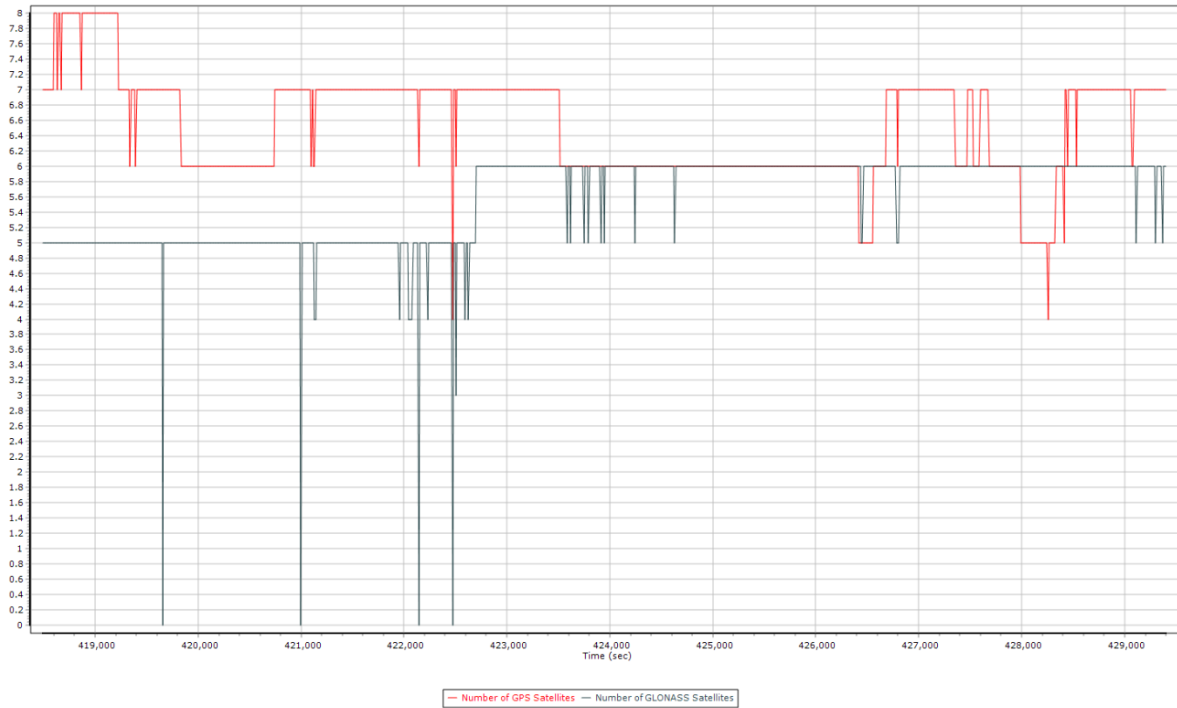
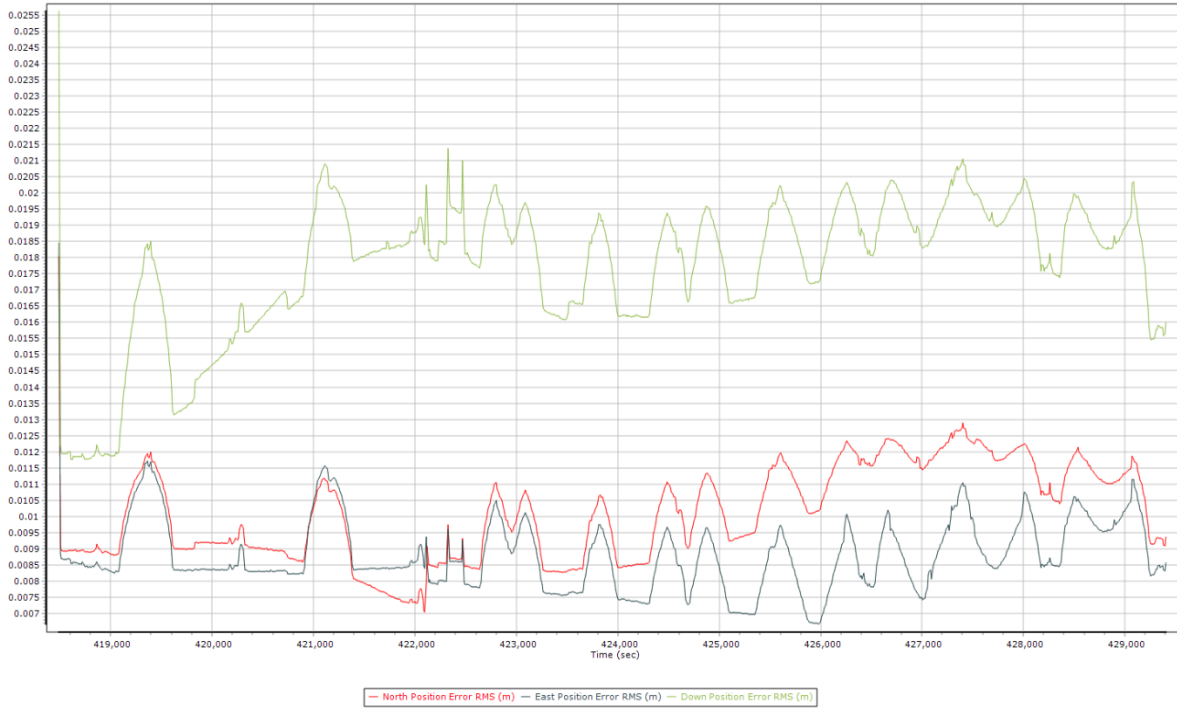
X:

Y:

Z:

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





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

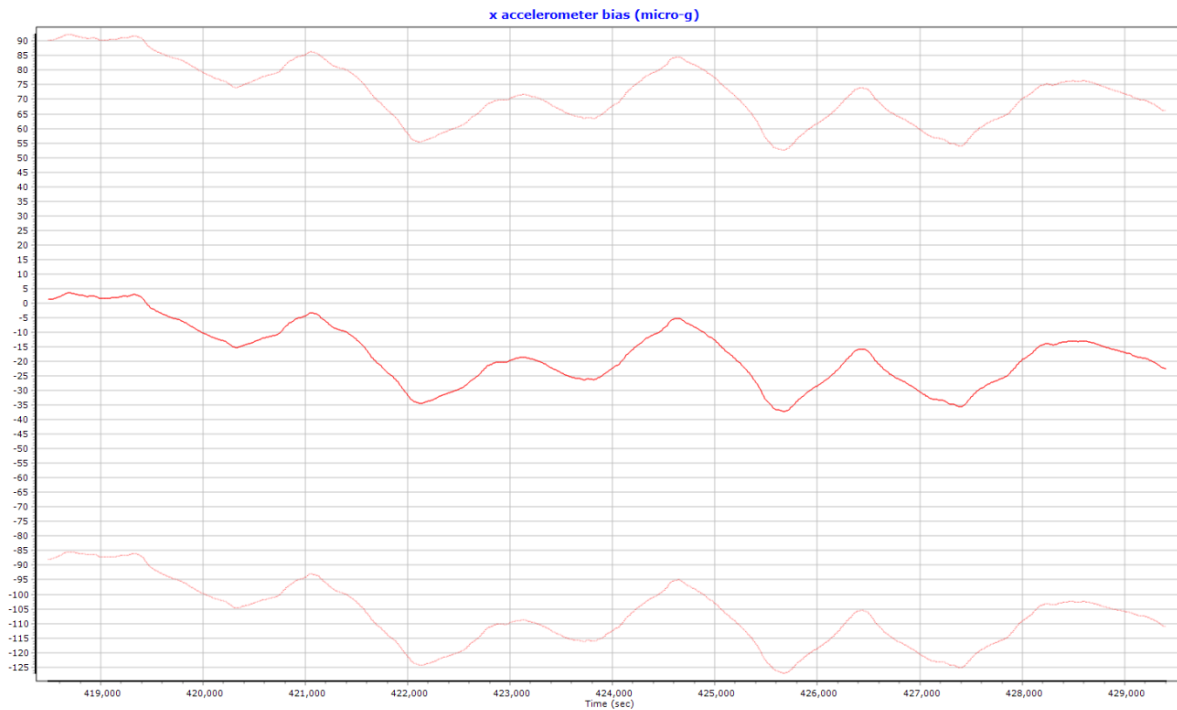
Start: 427280.000
End: 429413.087

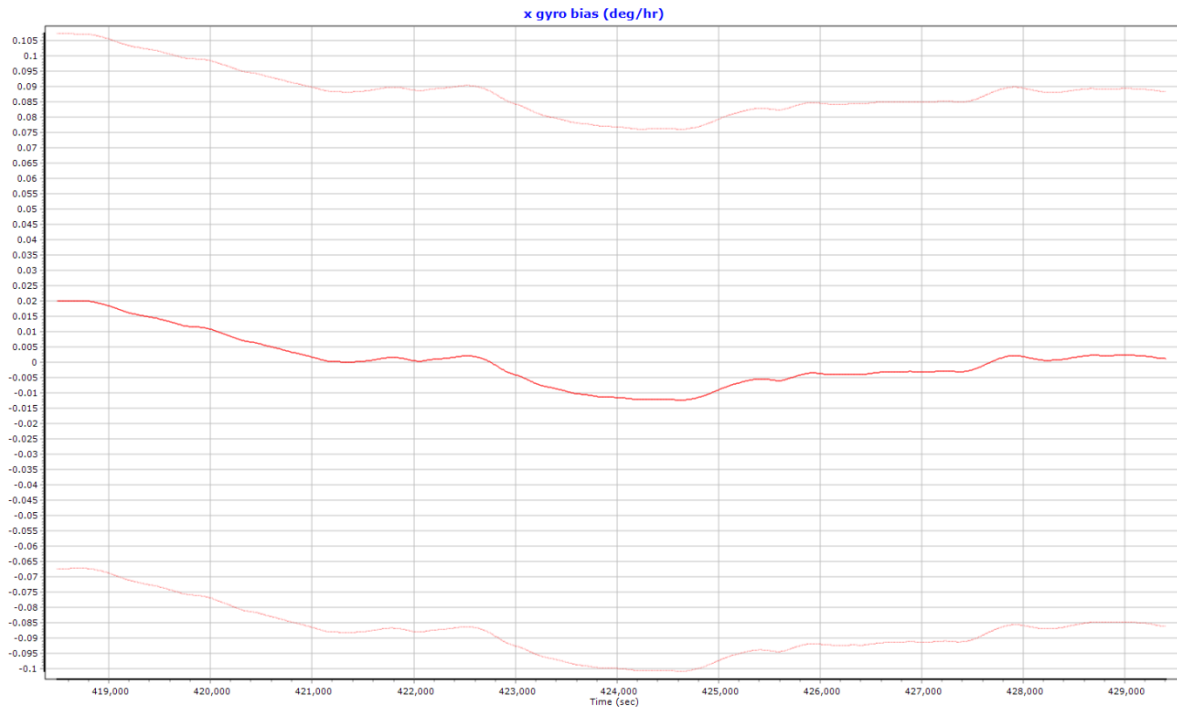
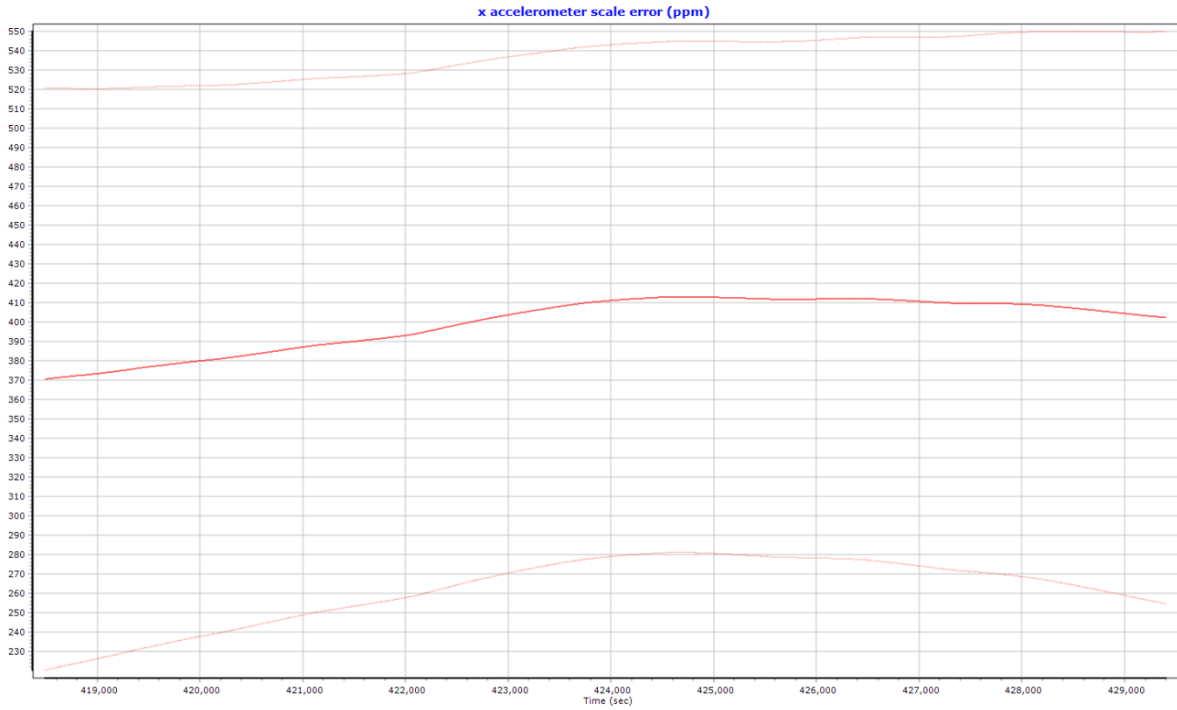
Entire time interval
 Seconds of start week

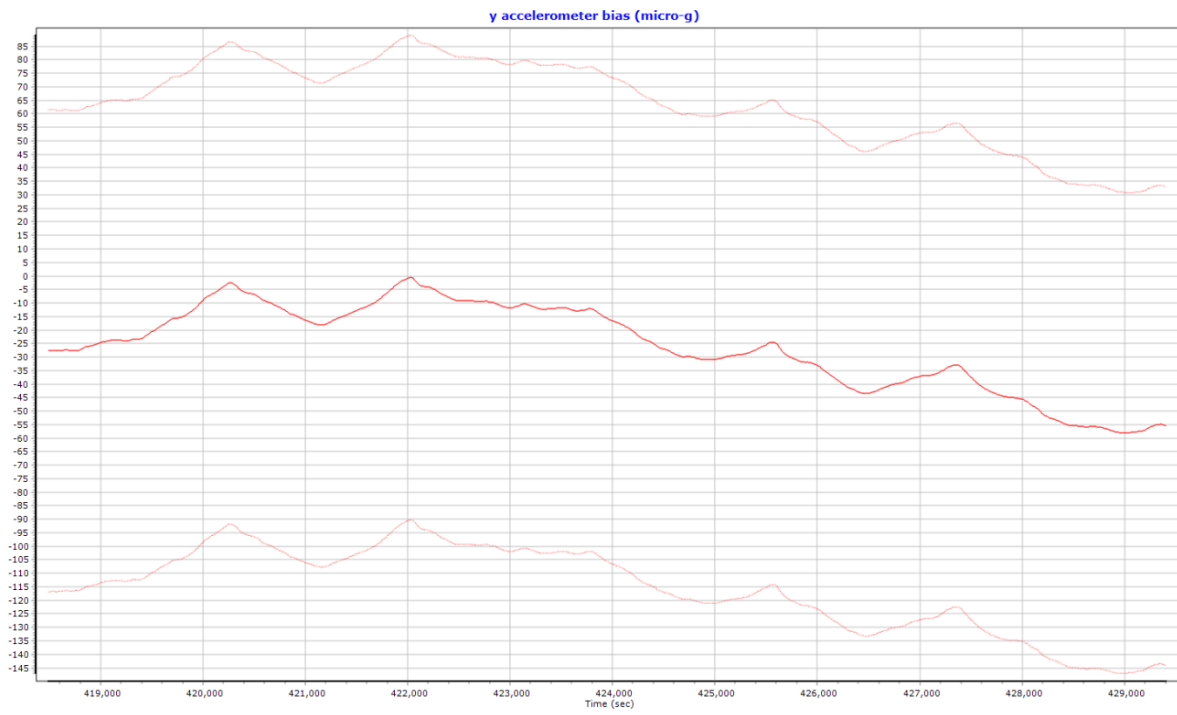
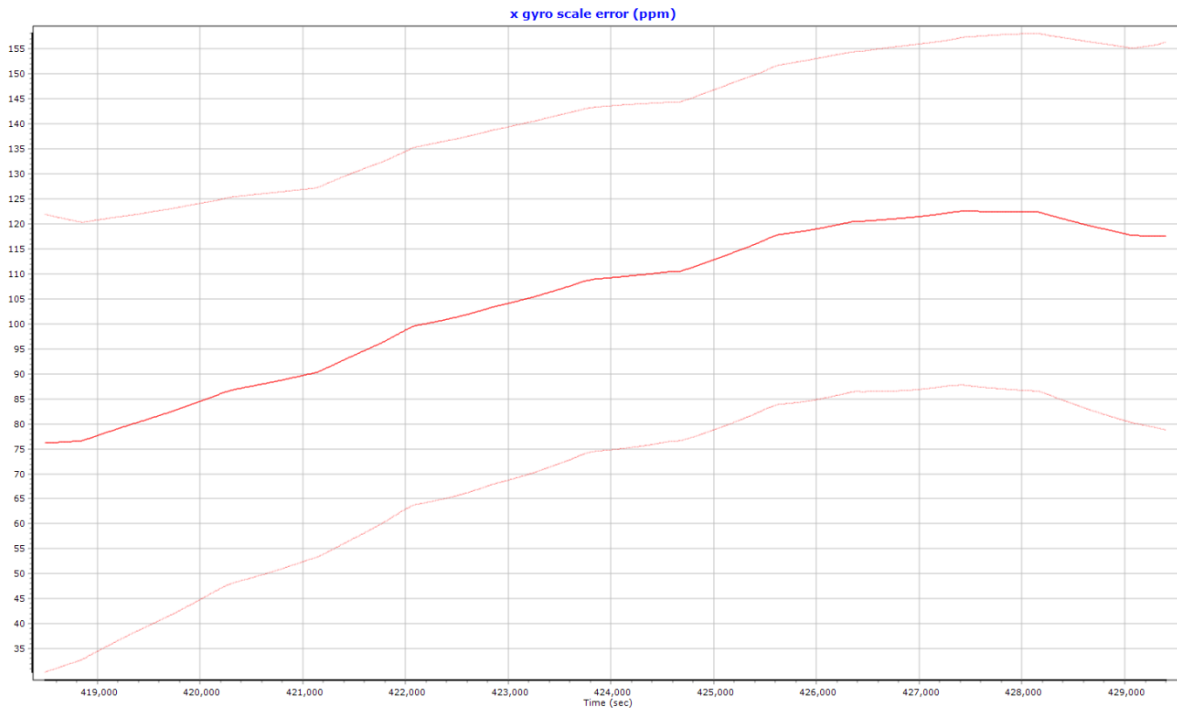
UTC Offset: 18.000

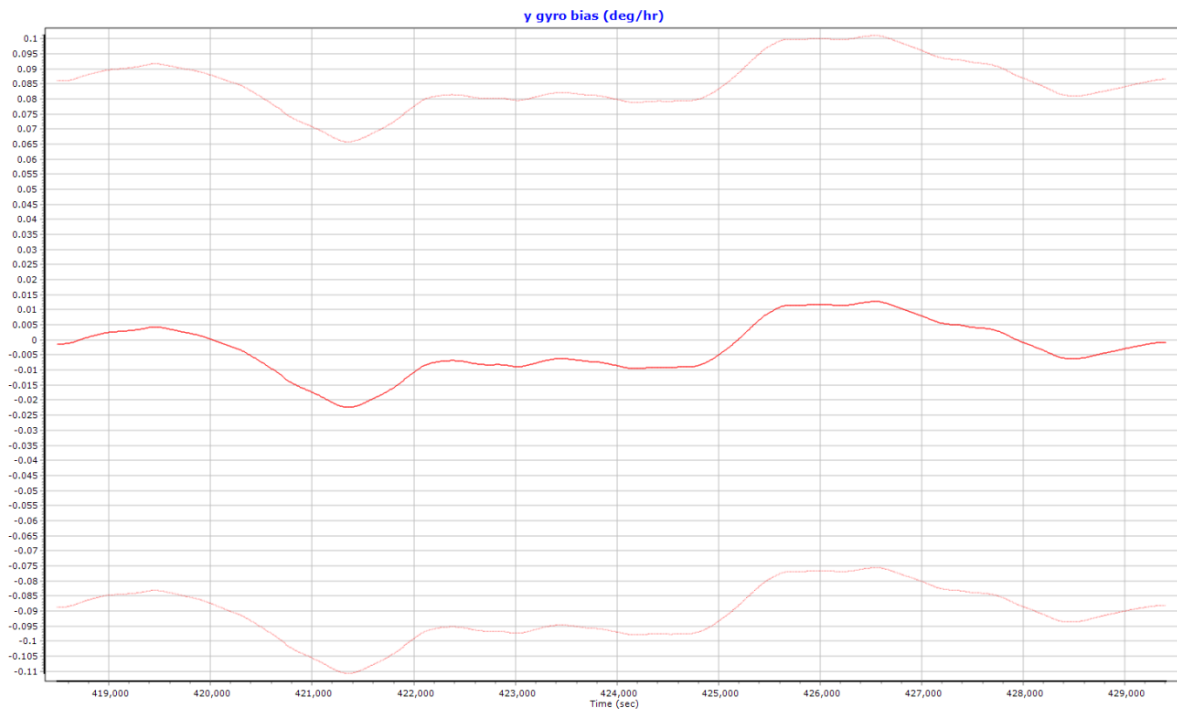
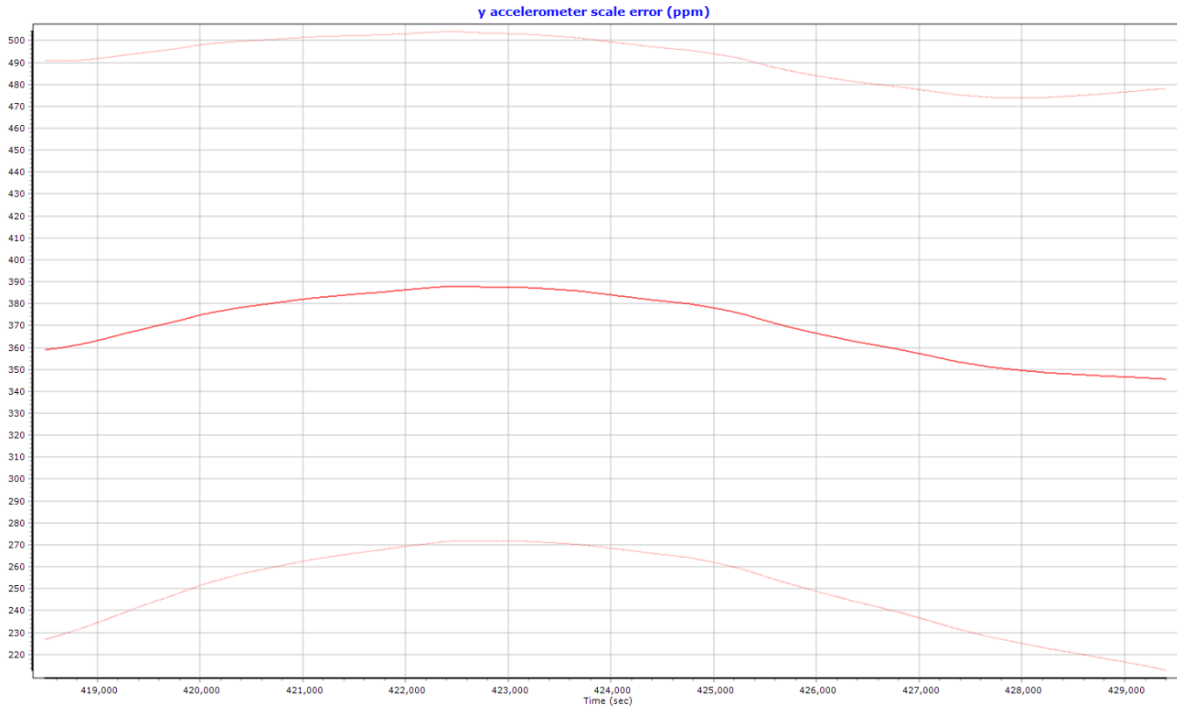
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

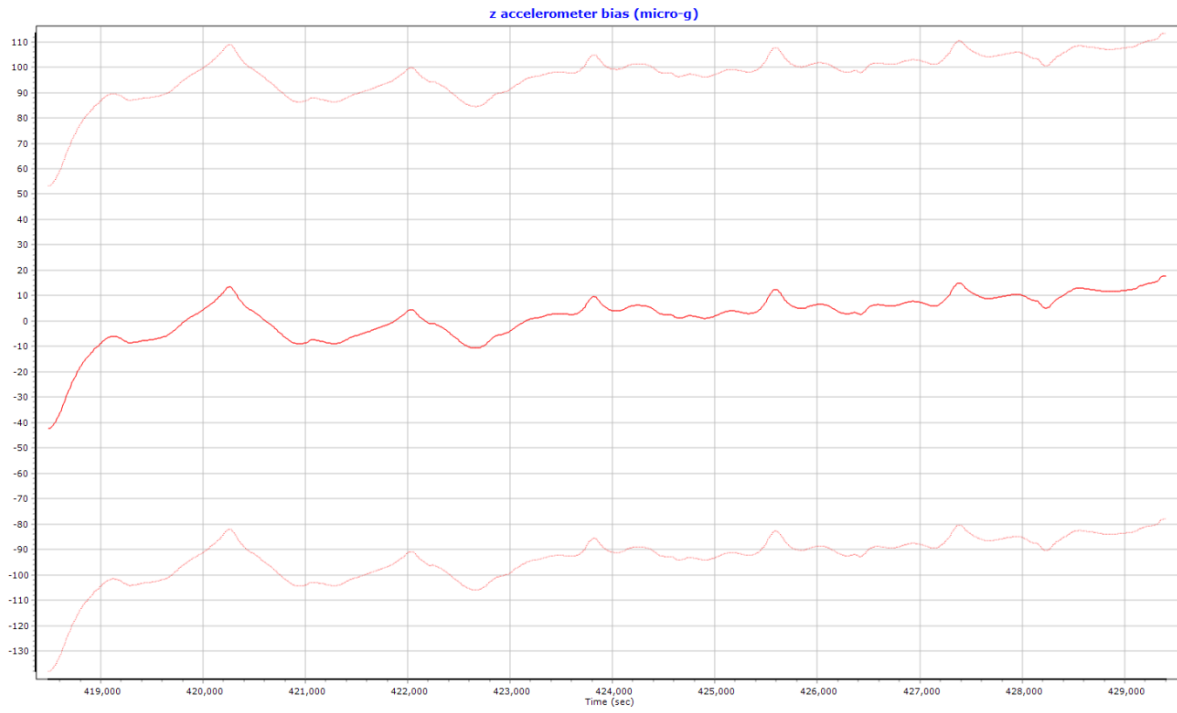
OK Cancel

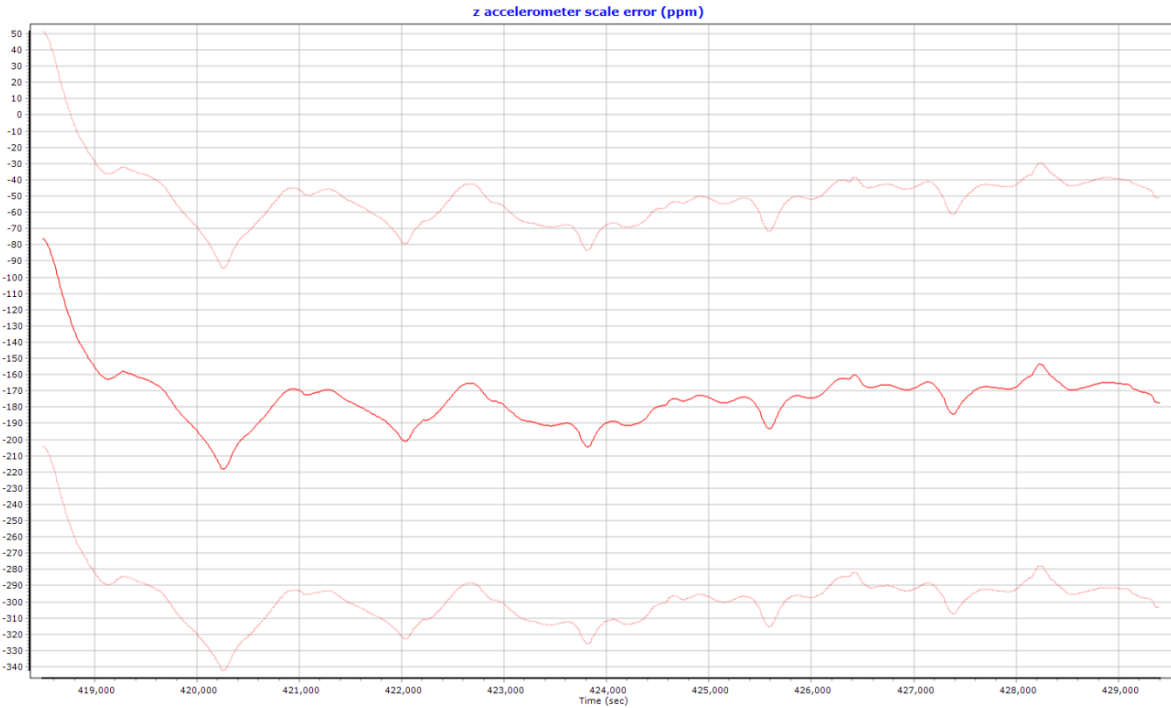


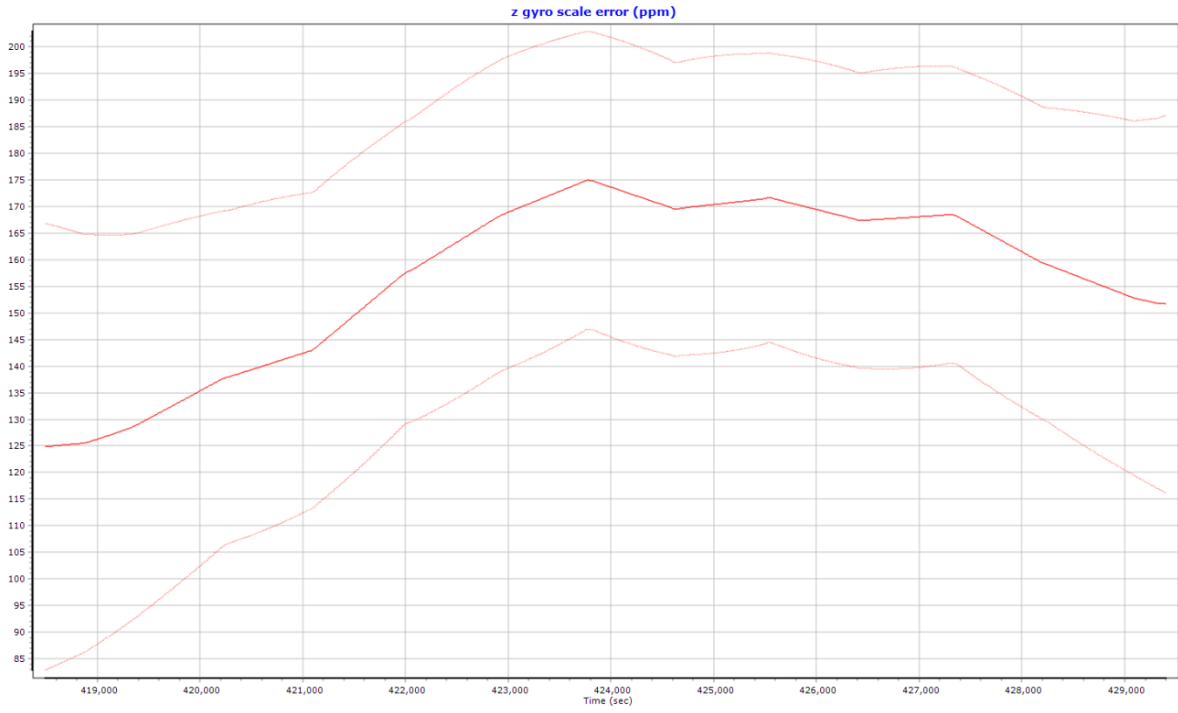




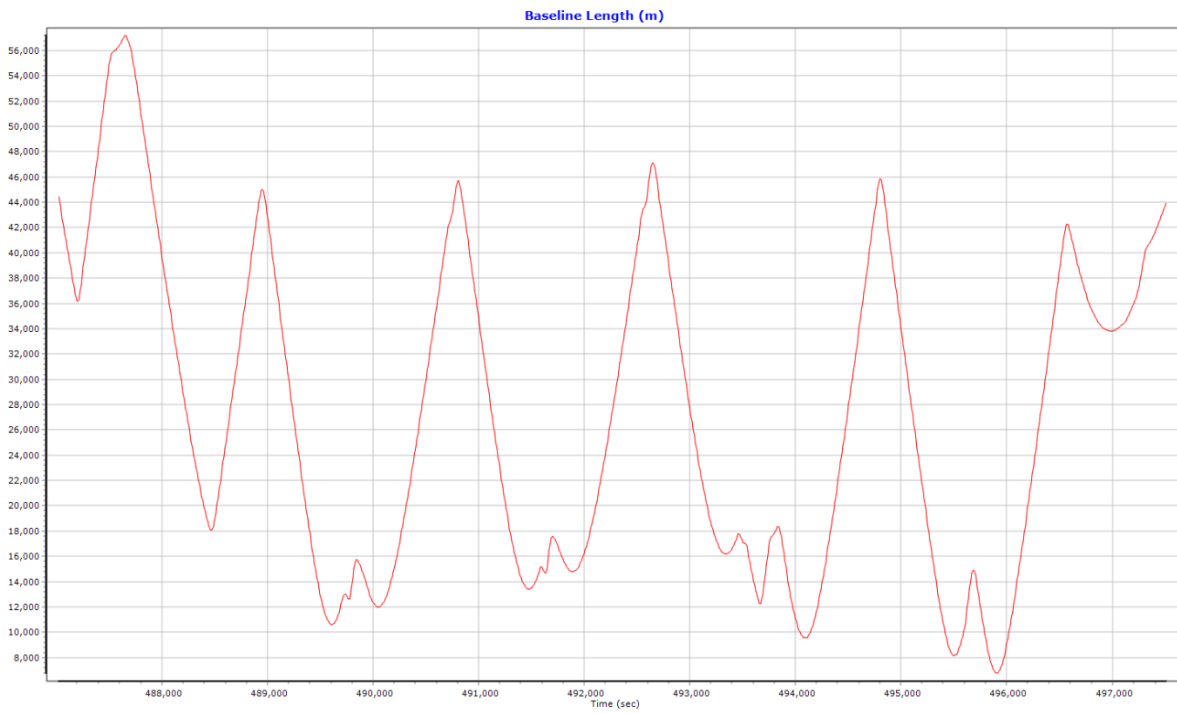
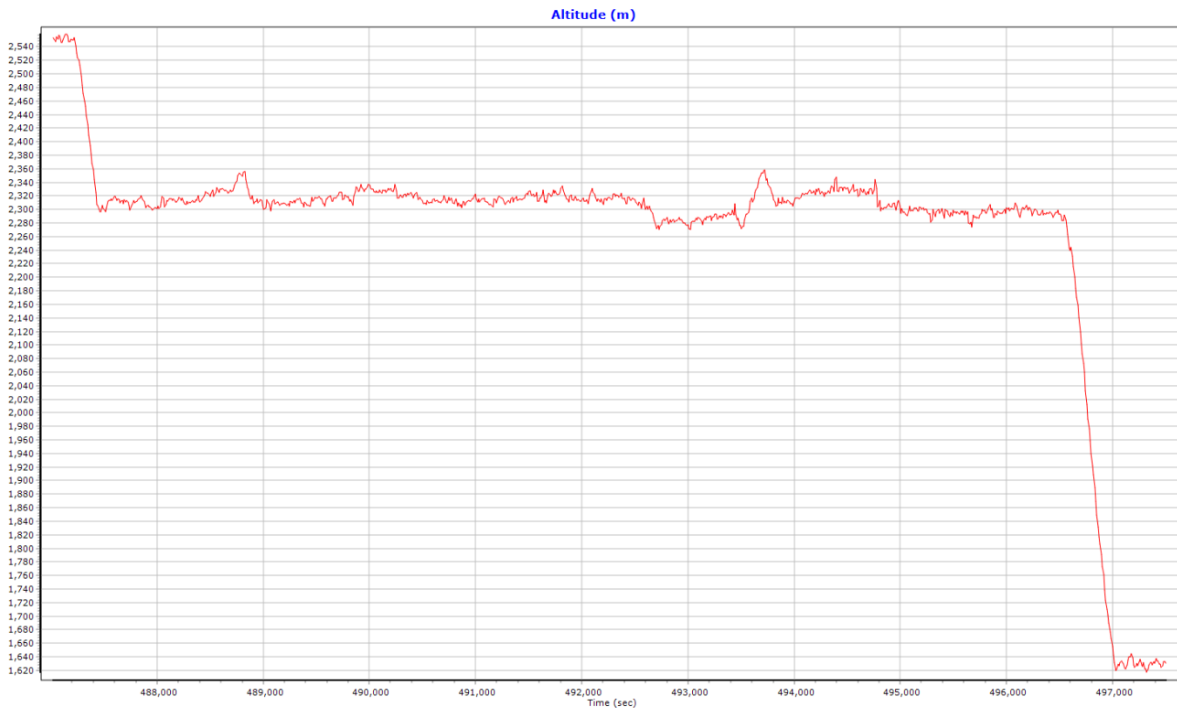


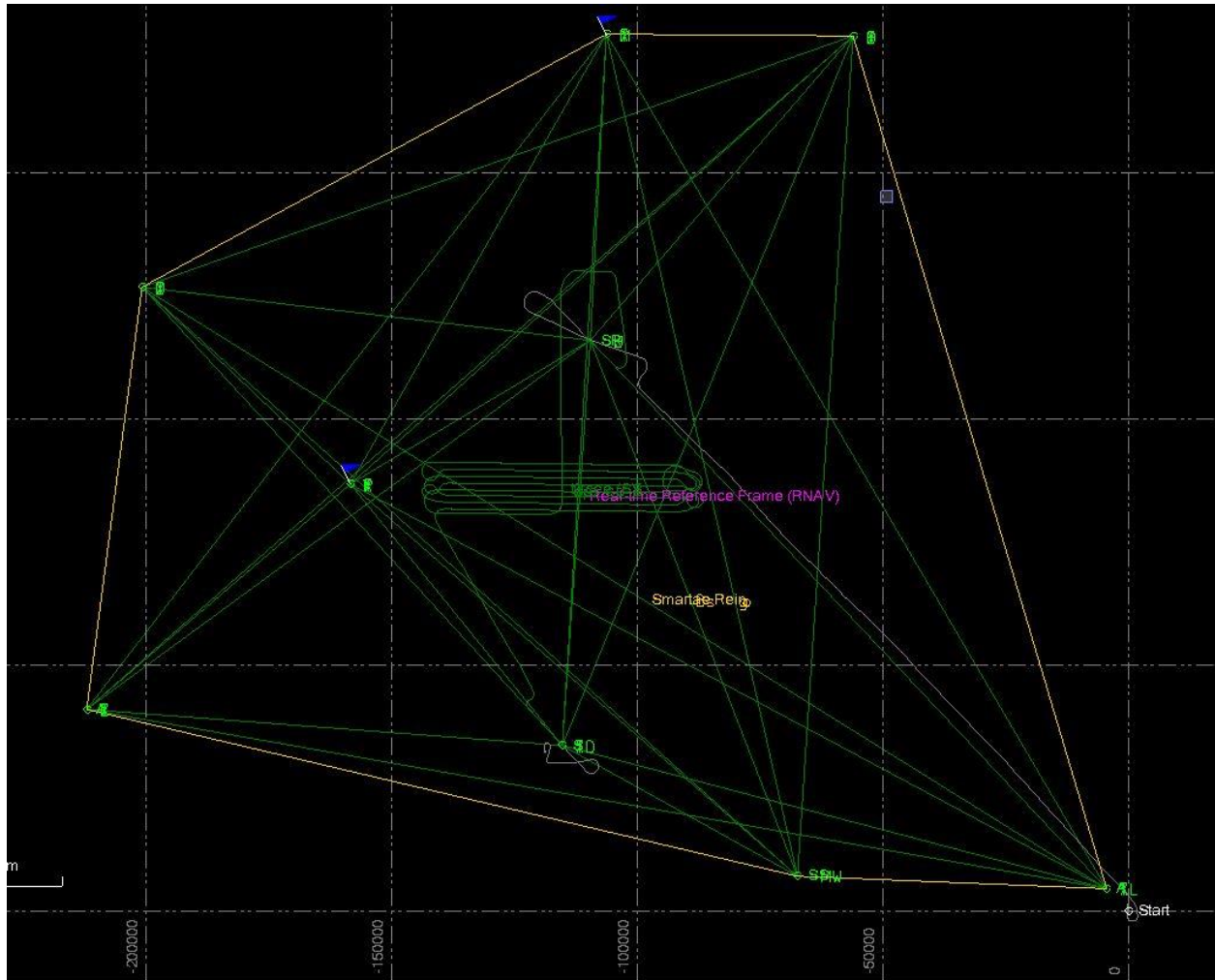


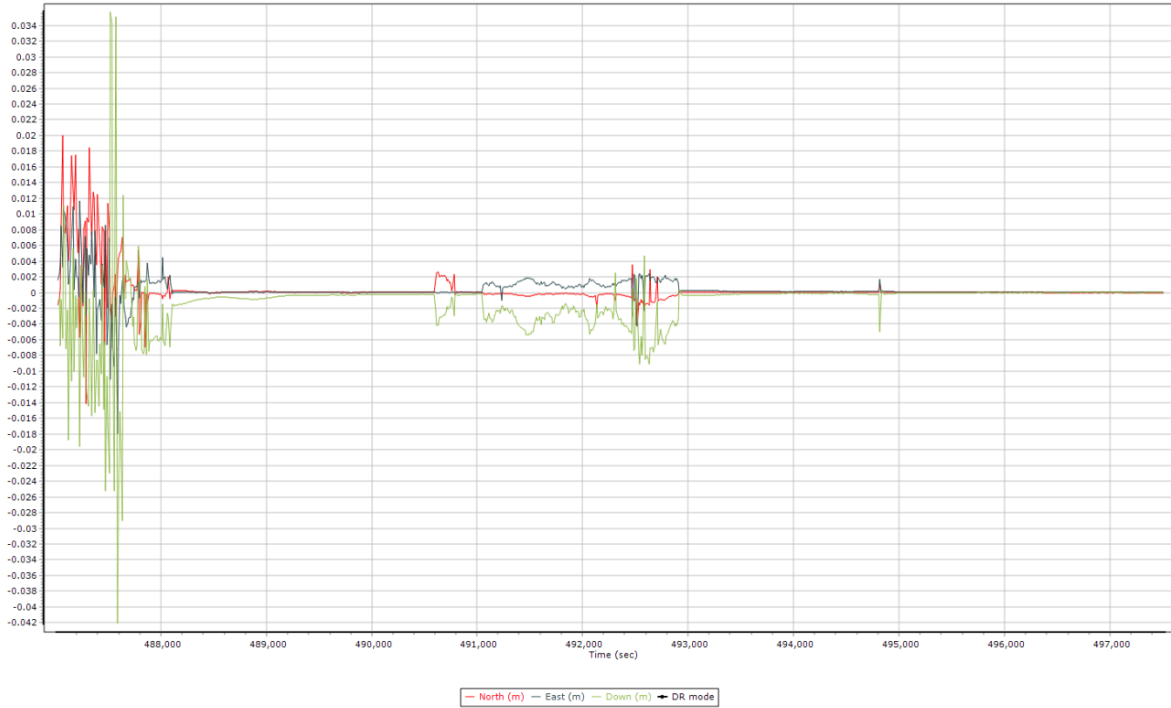




RBV18061A







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:

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

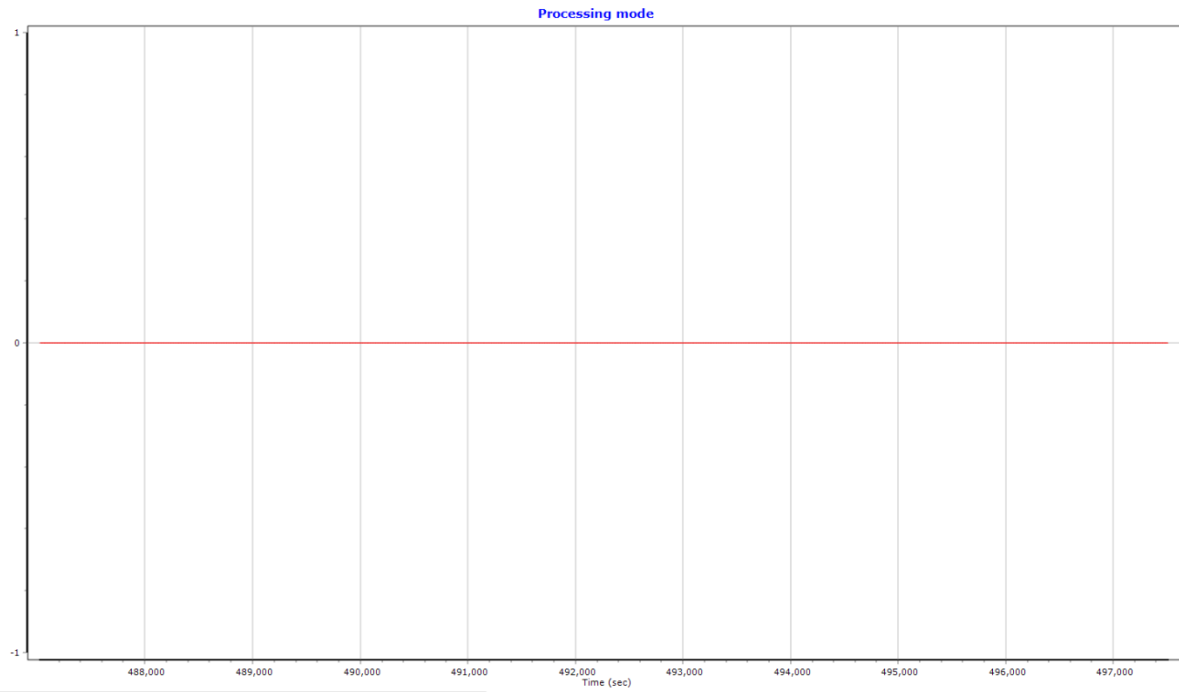
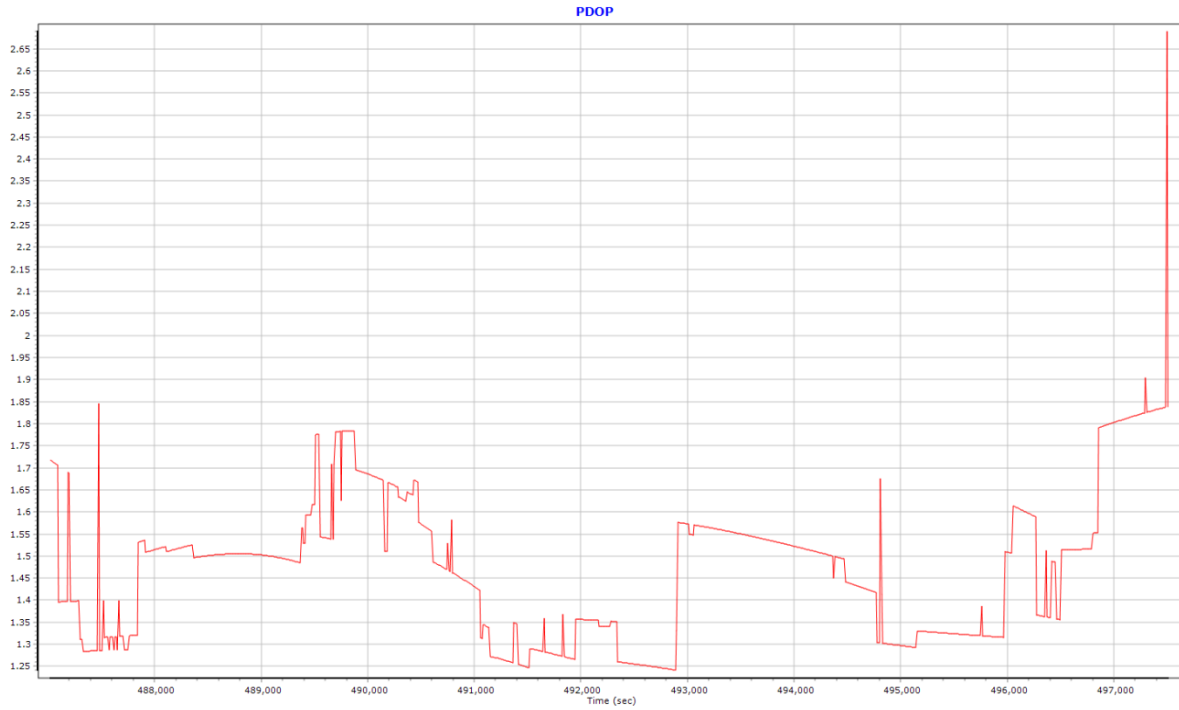
Aircraft to Stabilized Mount Mounting Angles

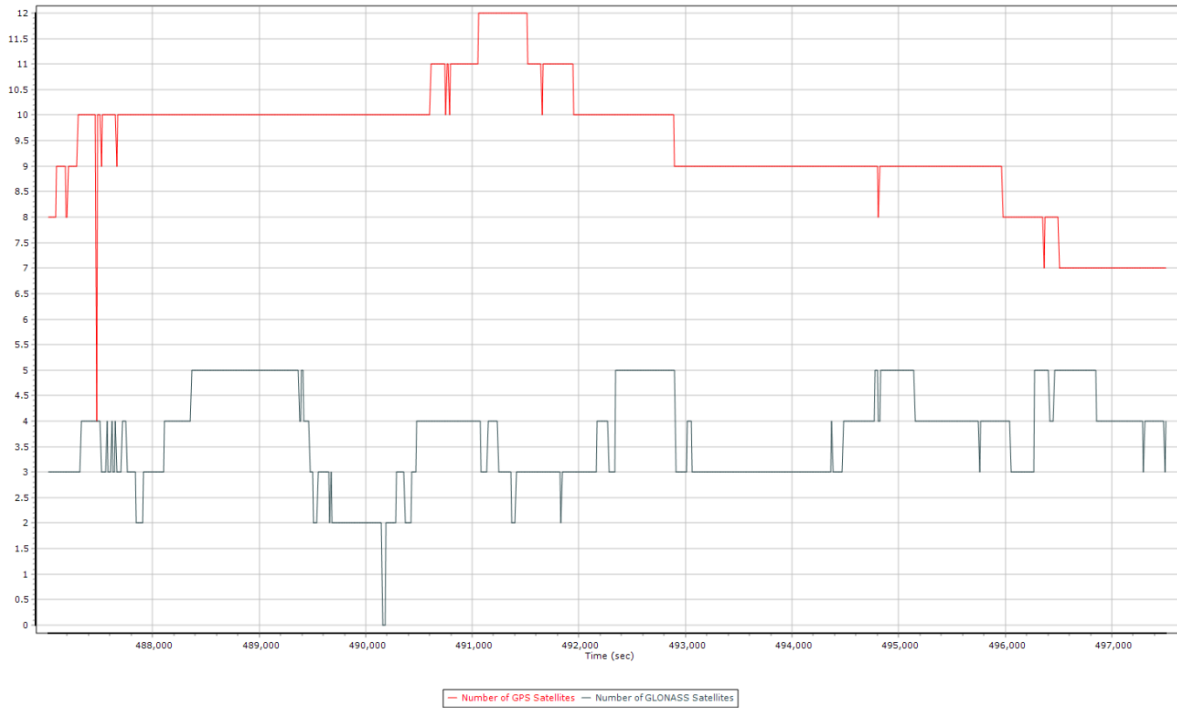
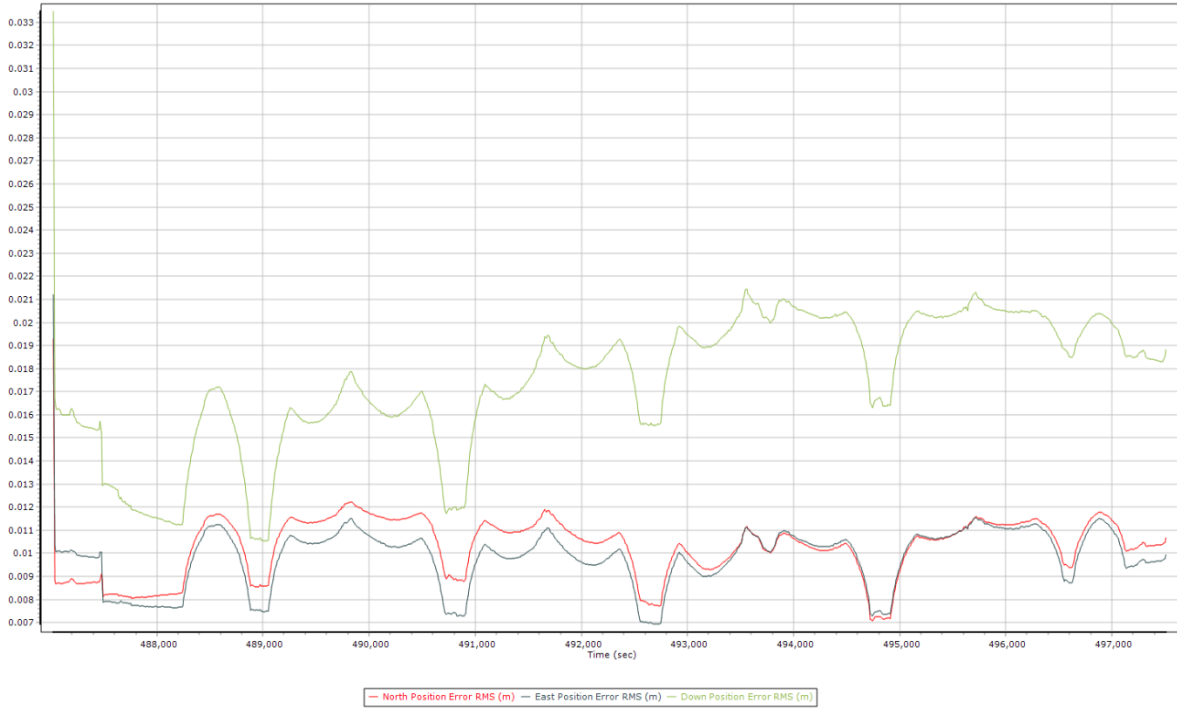
X:

Y:

Z:

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





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

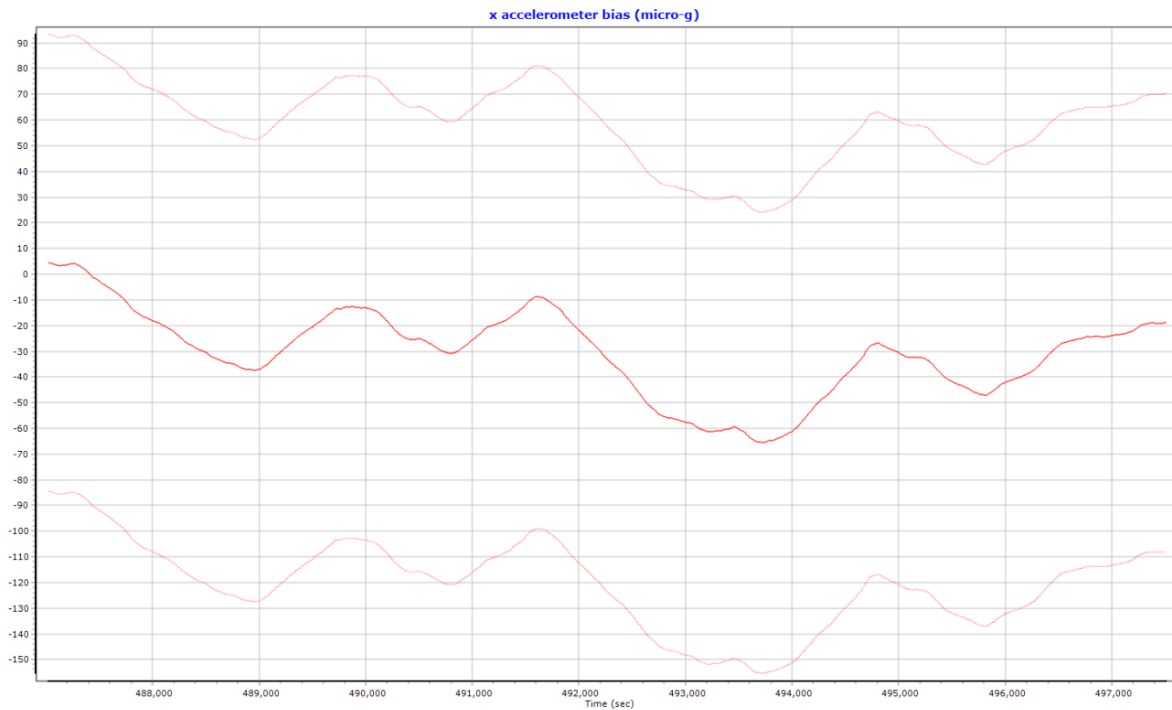
Start: 487021.379
End: 497518.809

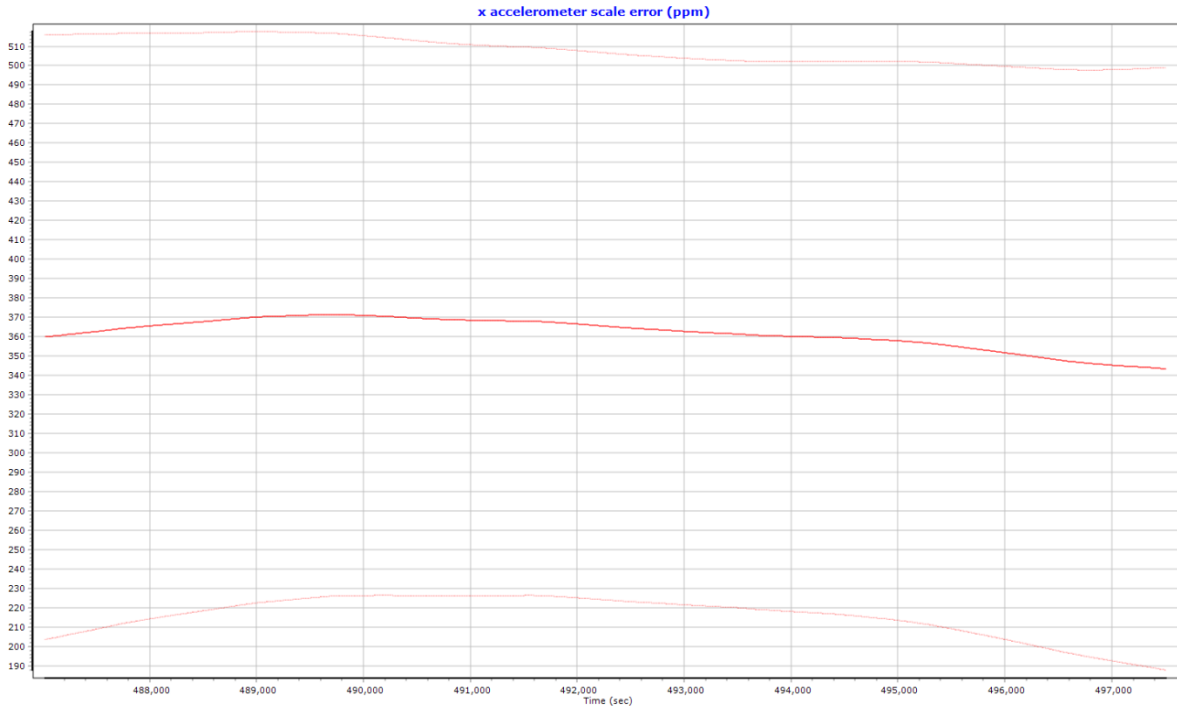
Entire time interval
 Seconds of start week

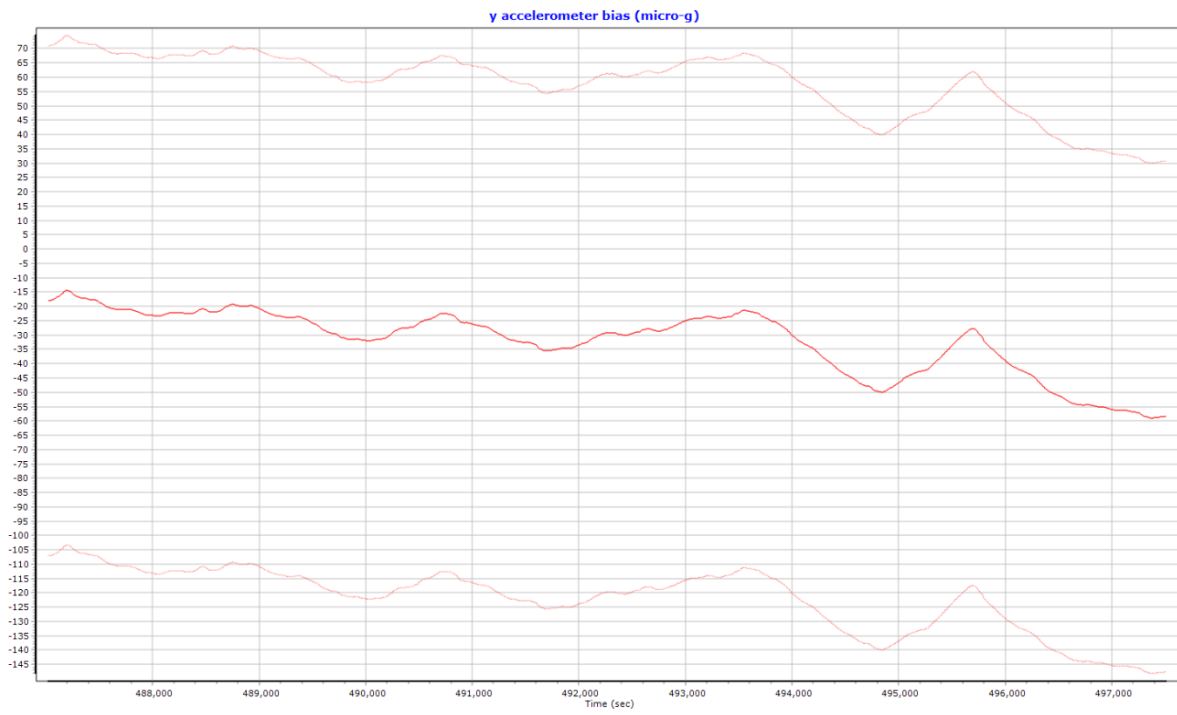
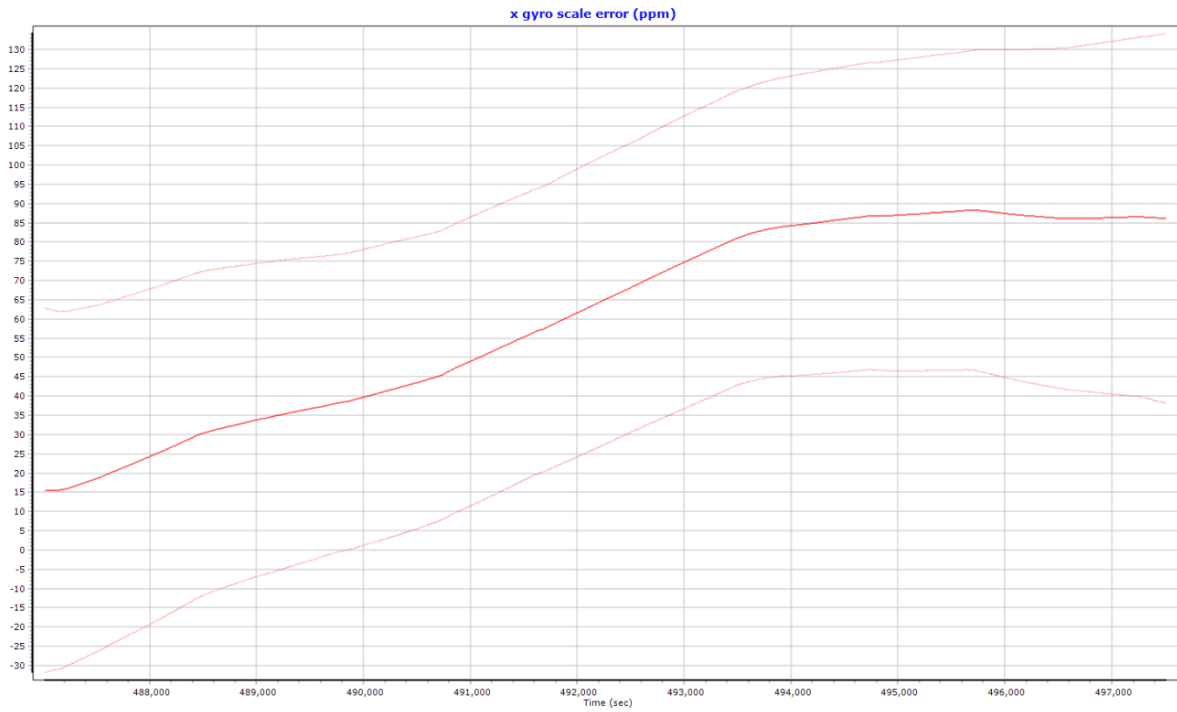
UTC Offset: 18.000

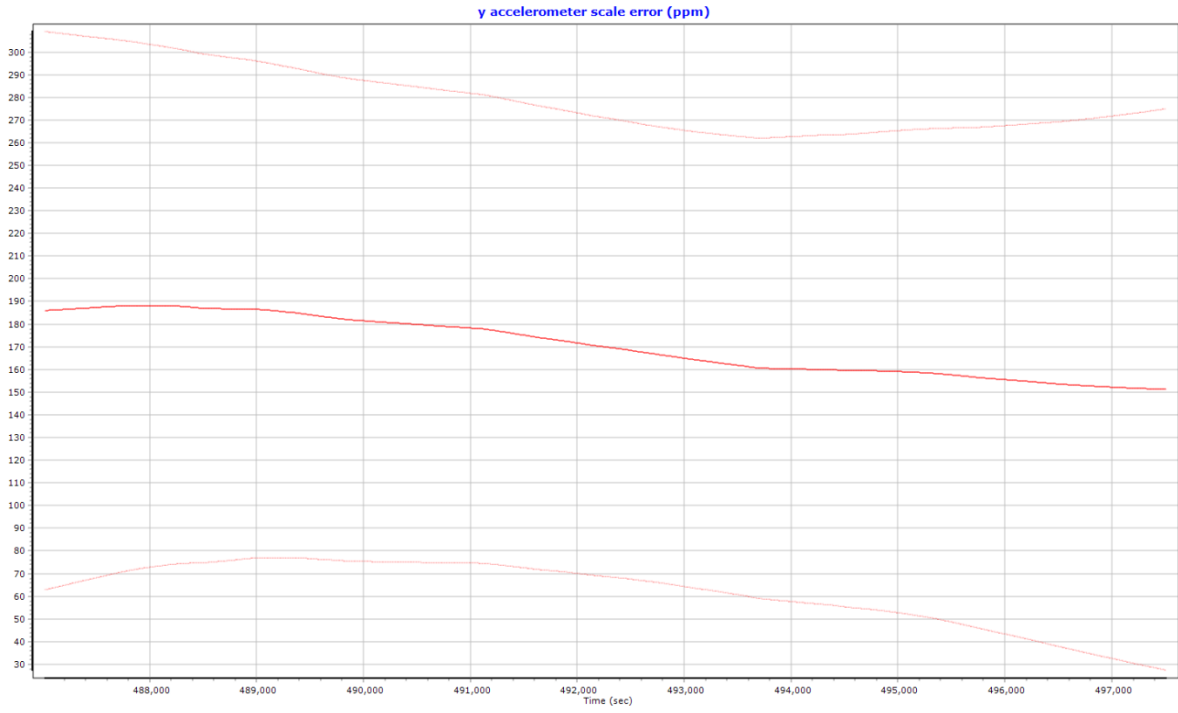
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

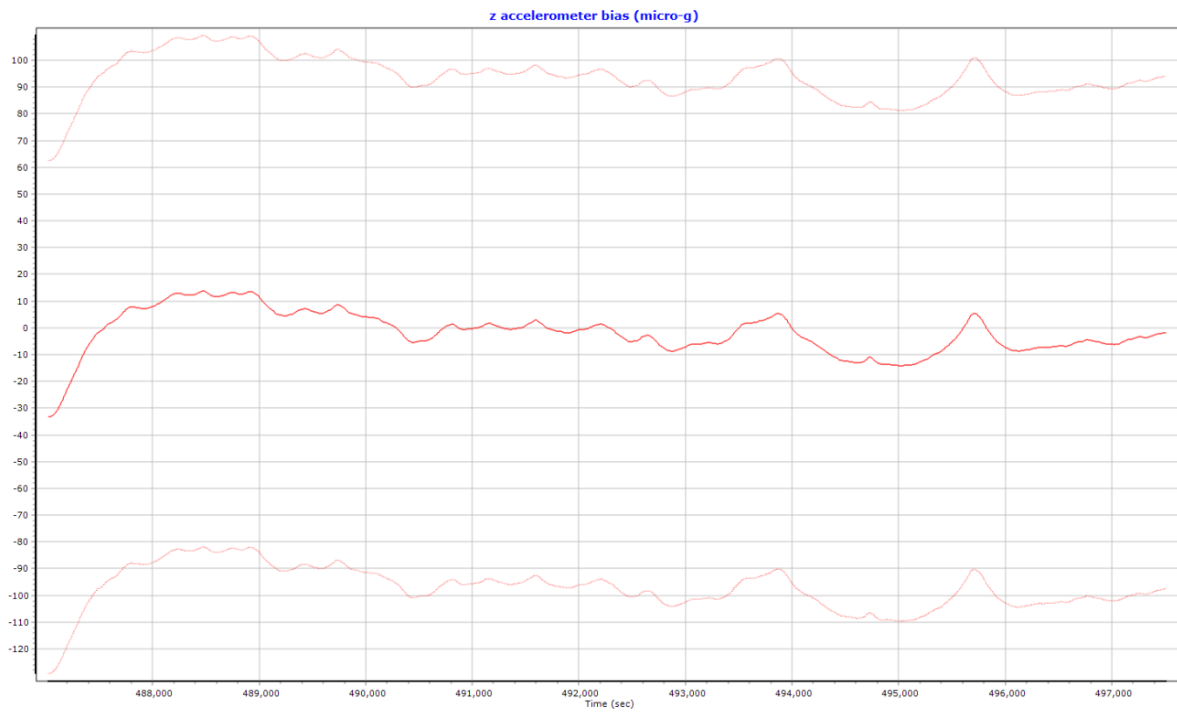
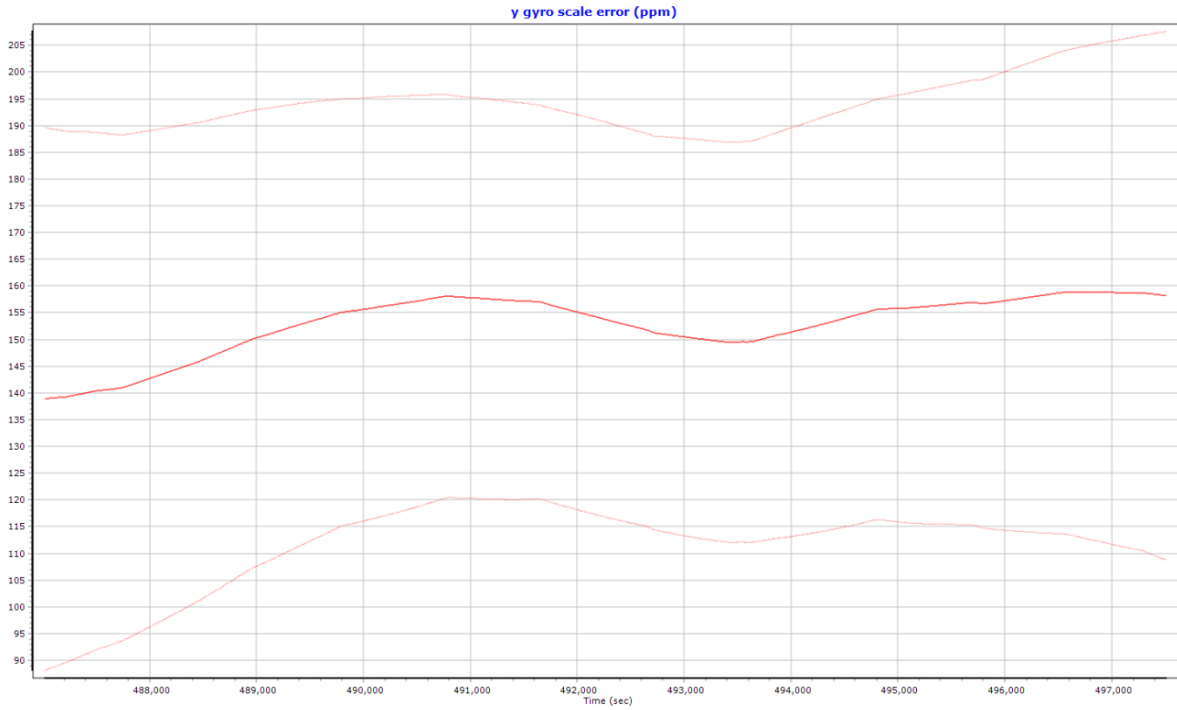
OK Cancel

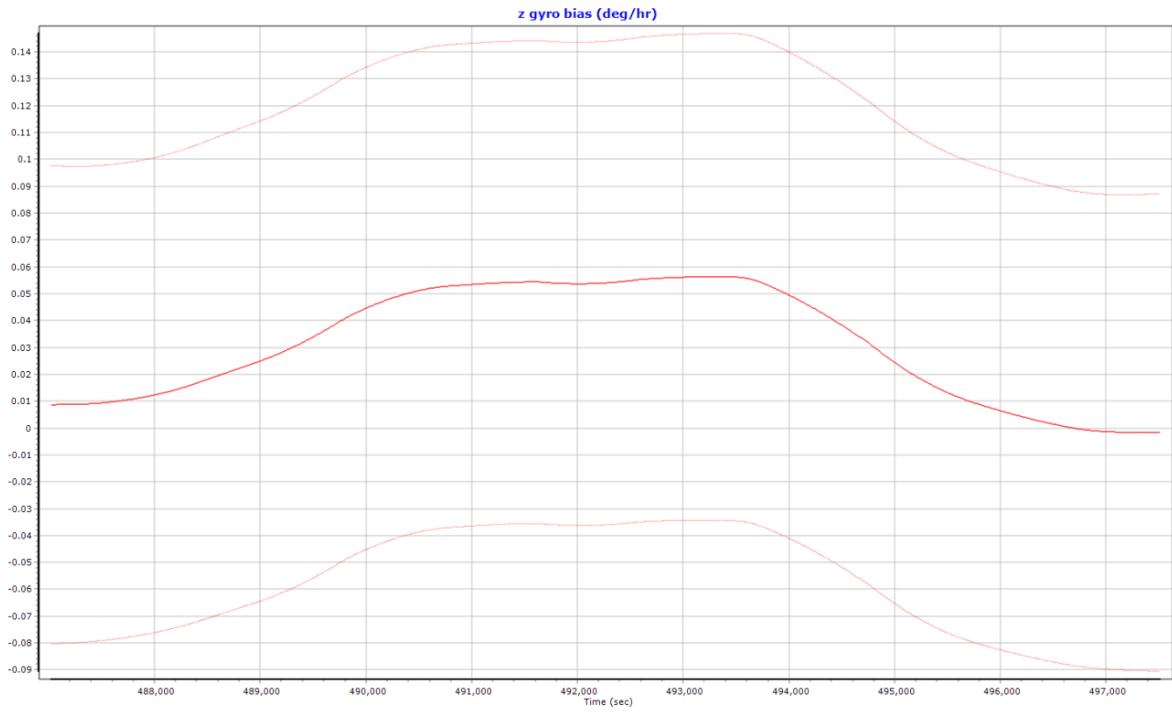
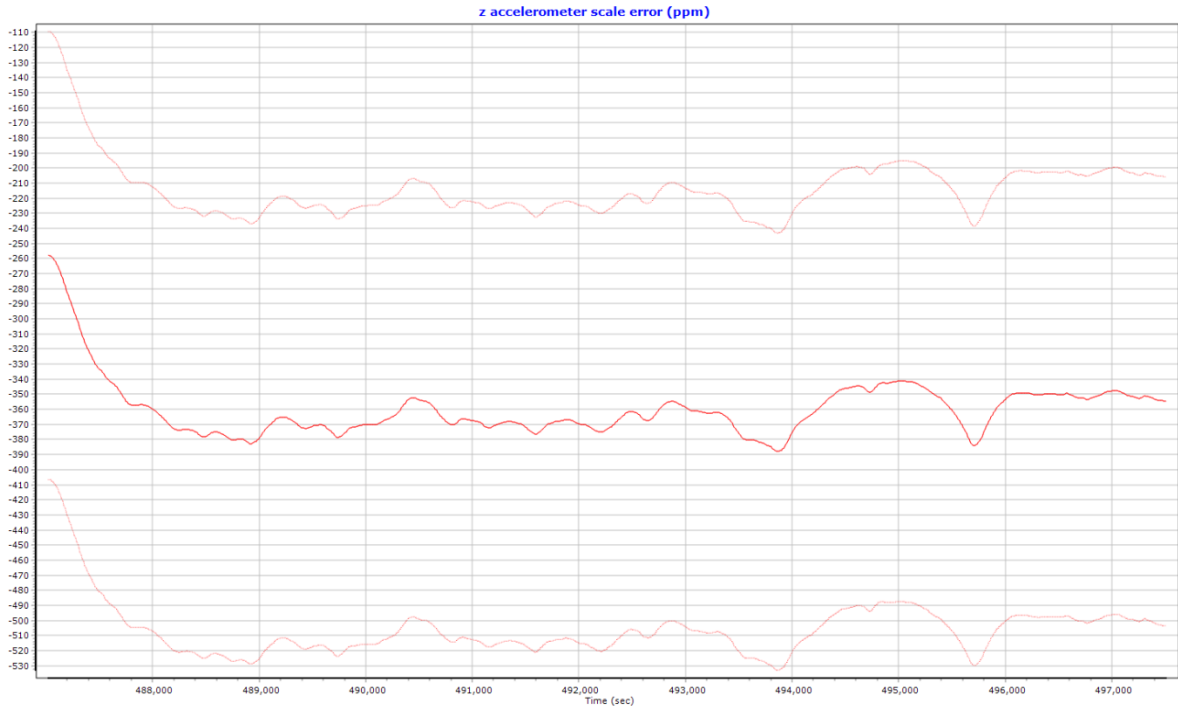


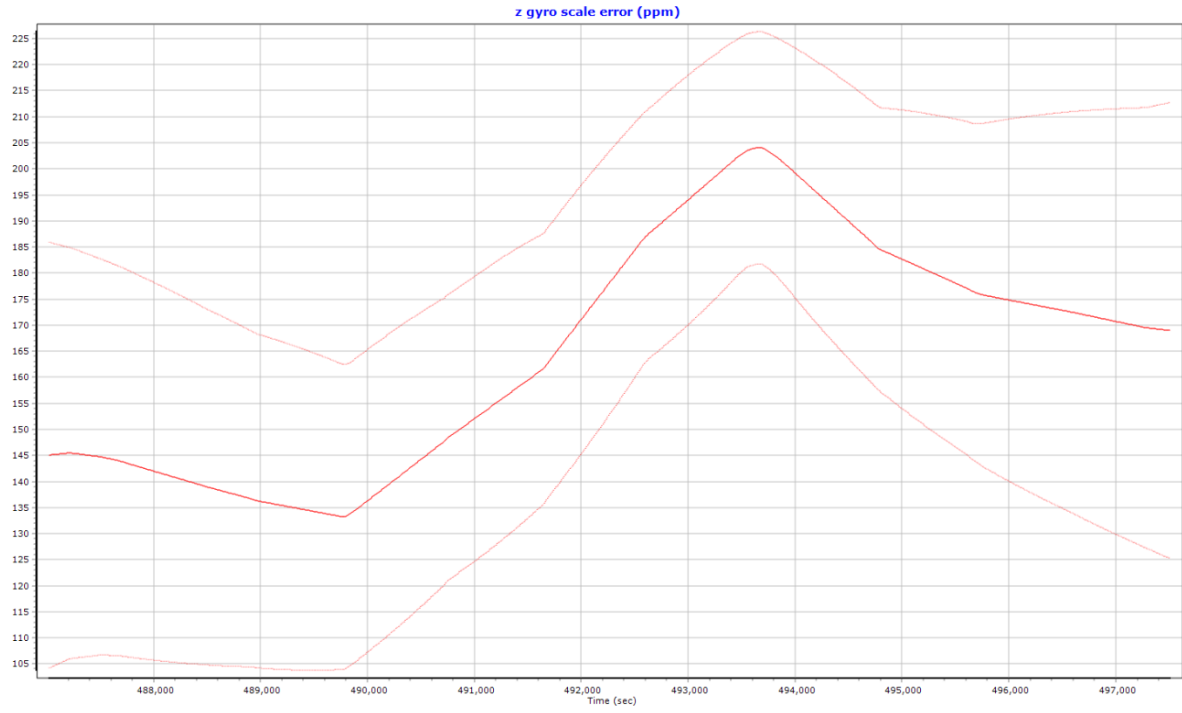




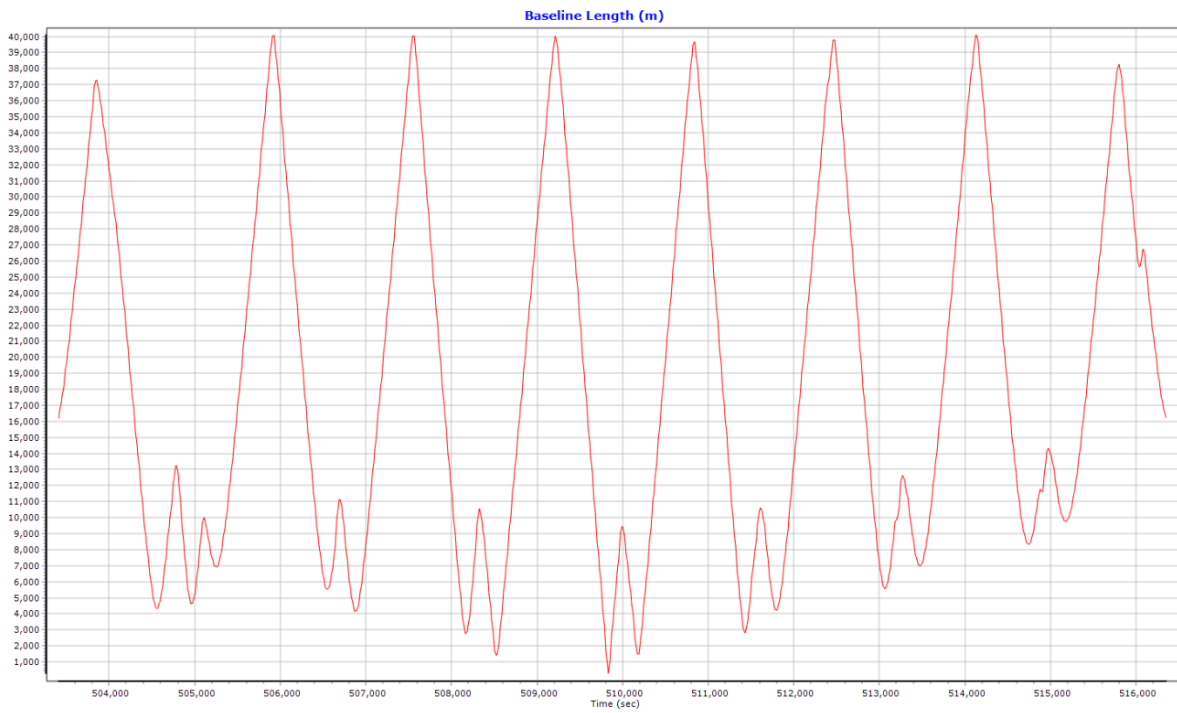
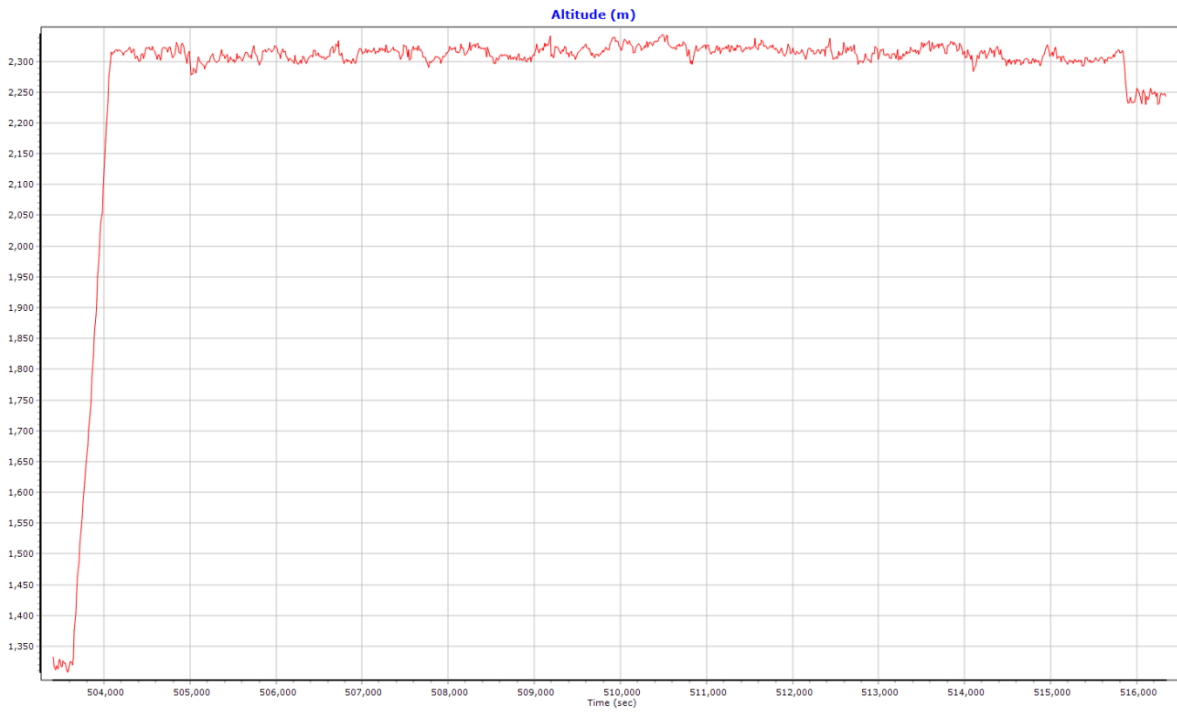


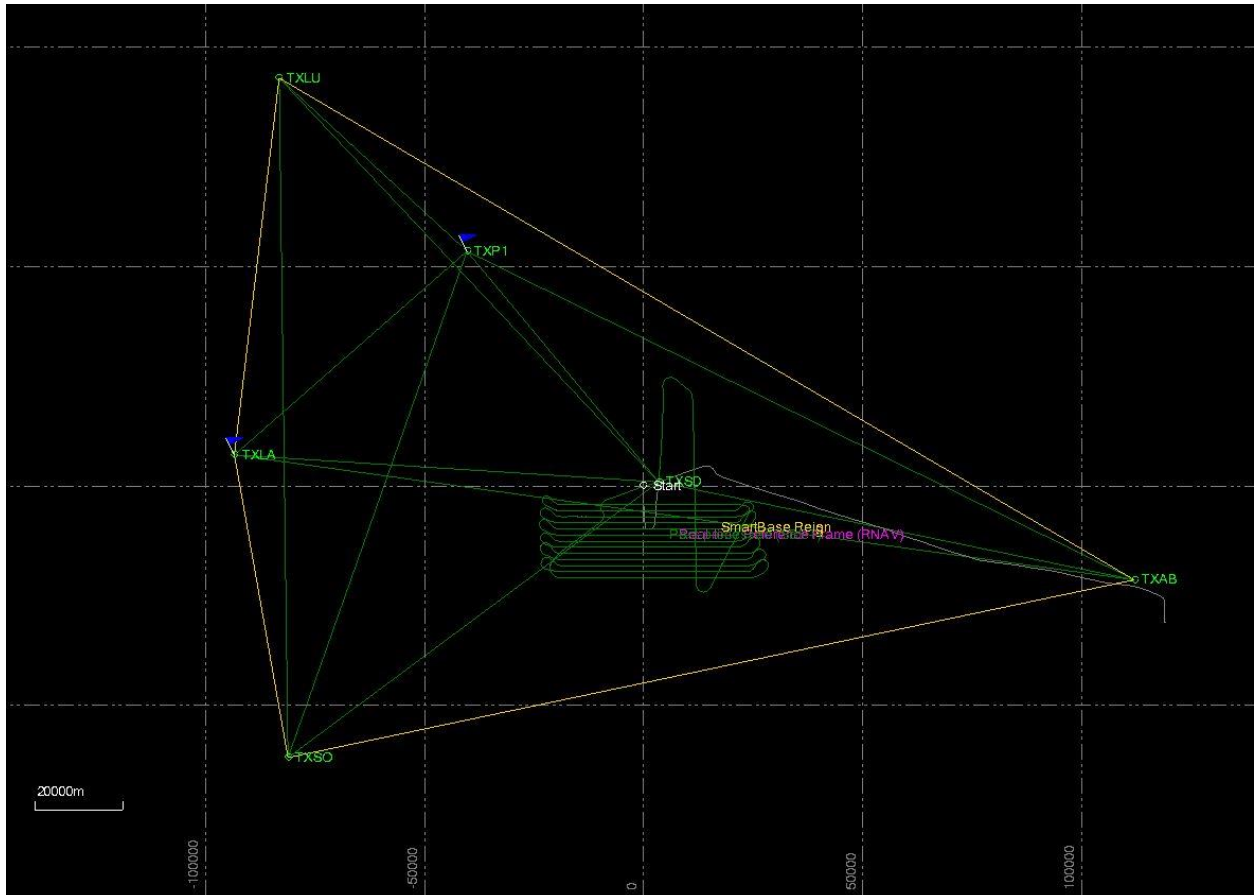






RBV18061B





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	0.000 m
Y	0.000 m
Z	0.000 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	-0.031 m
Y	0.004 m
Z	-0.611 m

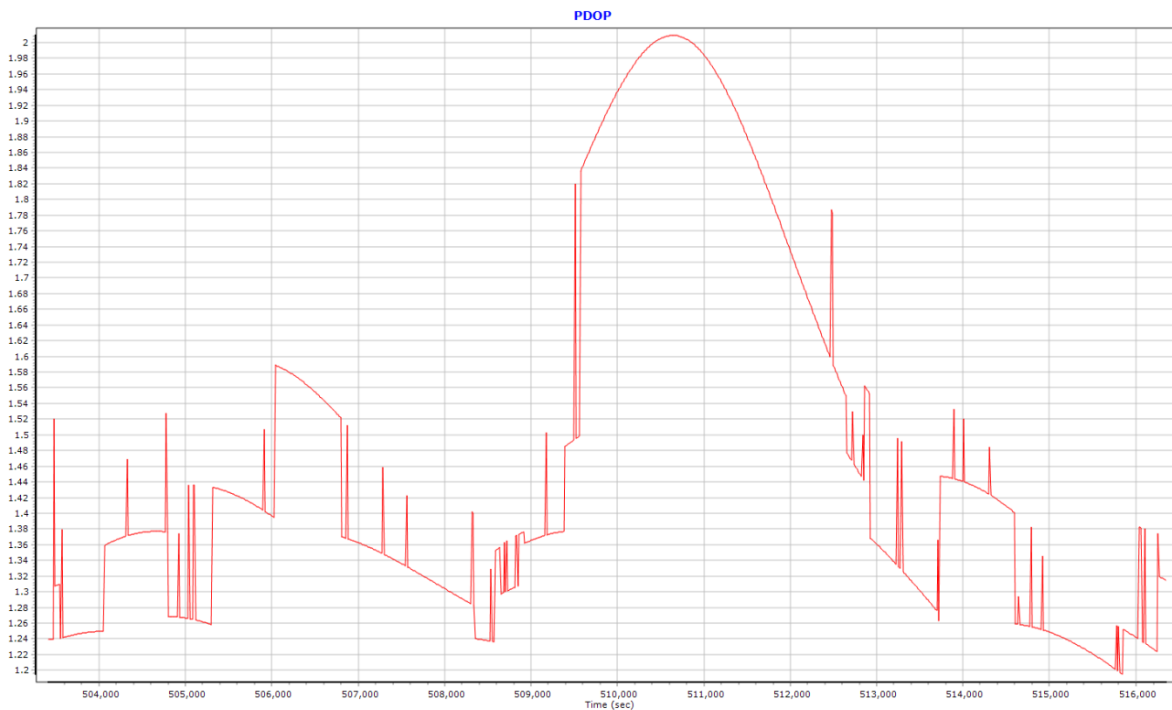
Aircraft to Stabilized Mount Mounting Angles

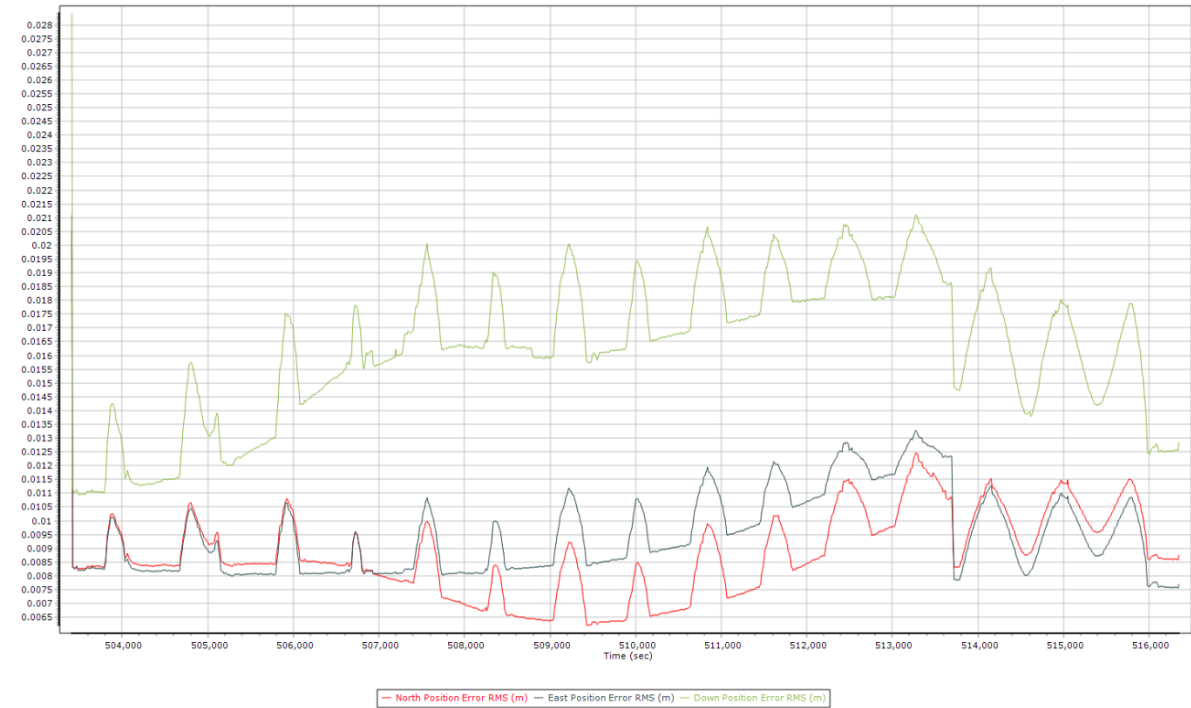
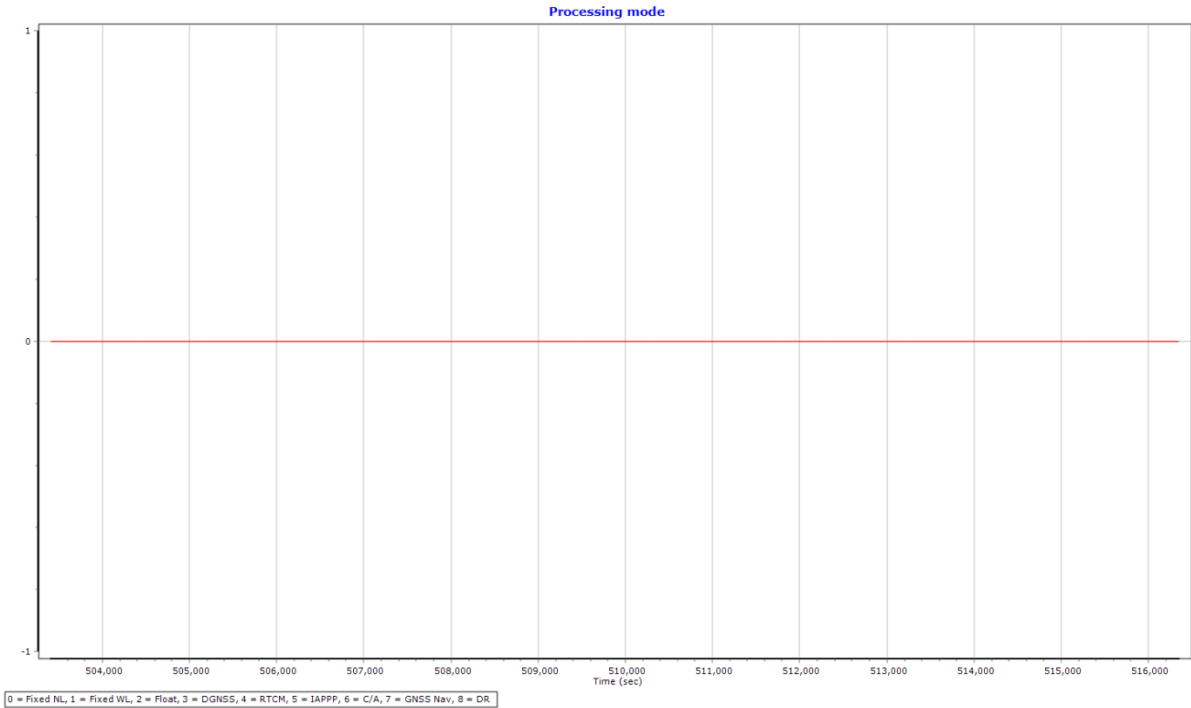
X	0.000 deg
Y	0.000 deg
Z	0.000 deg

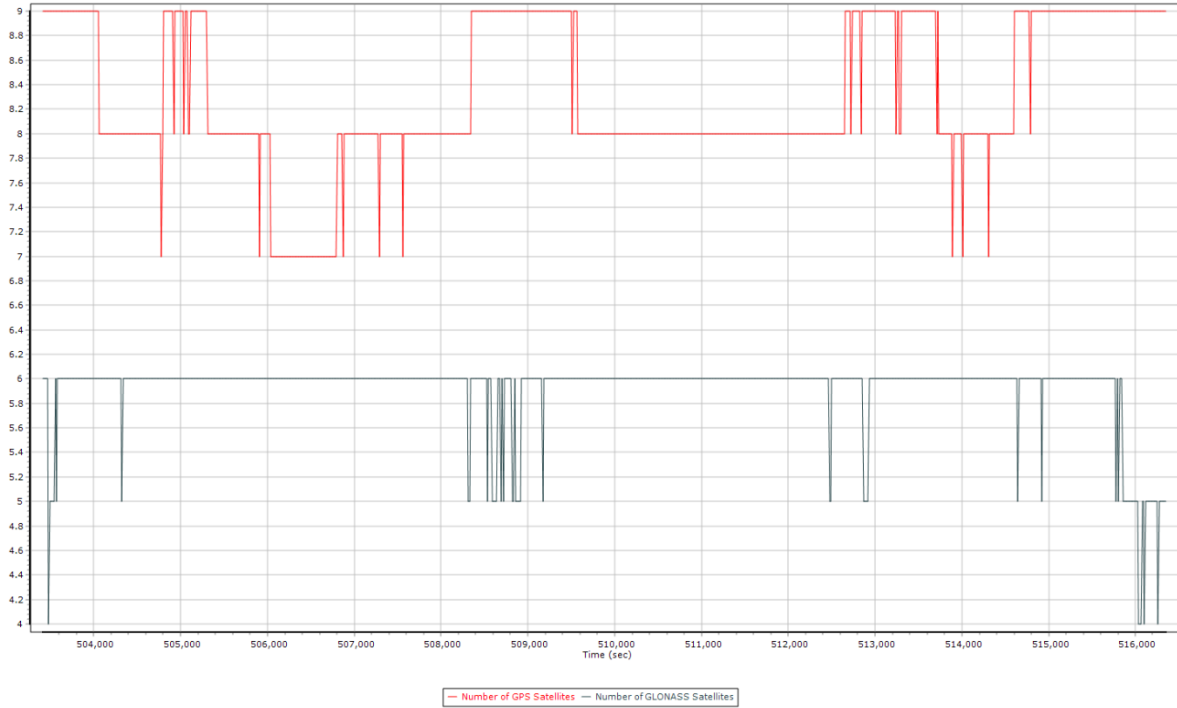
Standard Deviation: <3cm 10cm 50cm 1m 10m

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

OK Cancel







Project Settings [X]

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

Timing

Start: 503409.884 Data: Incr. (sec) ▲

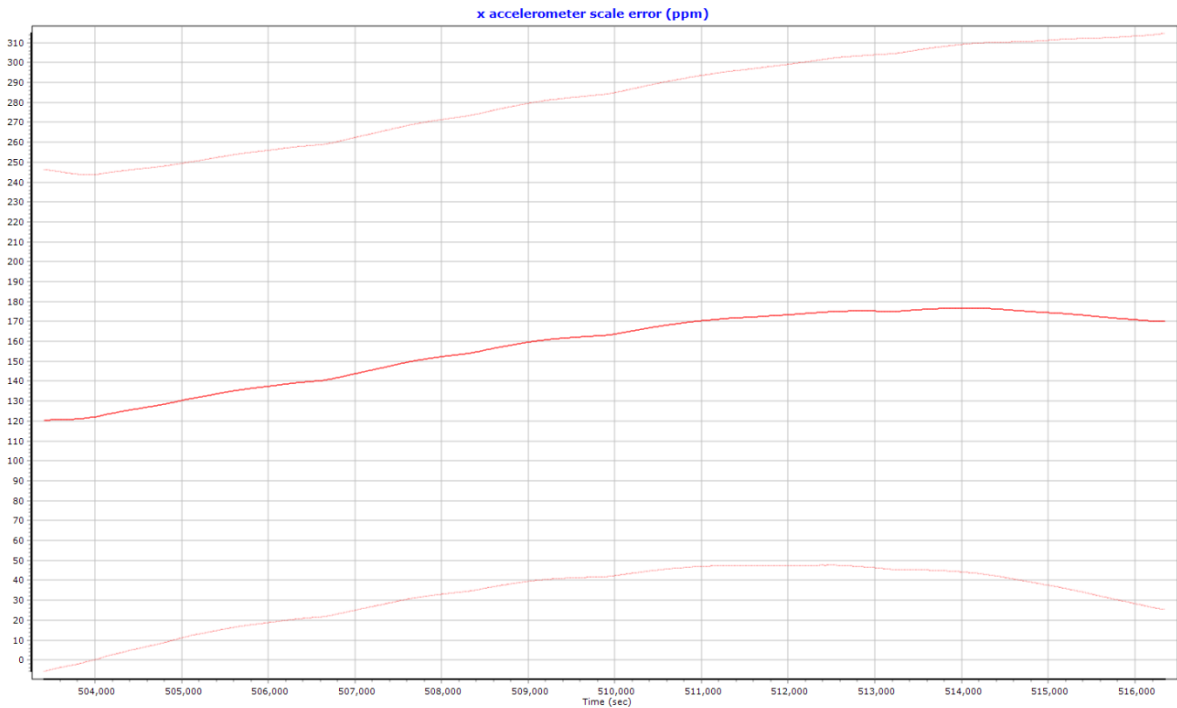
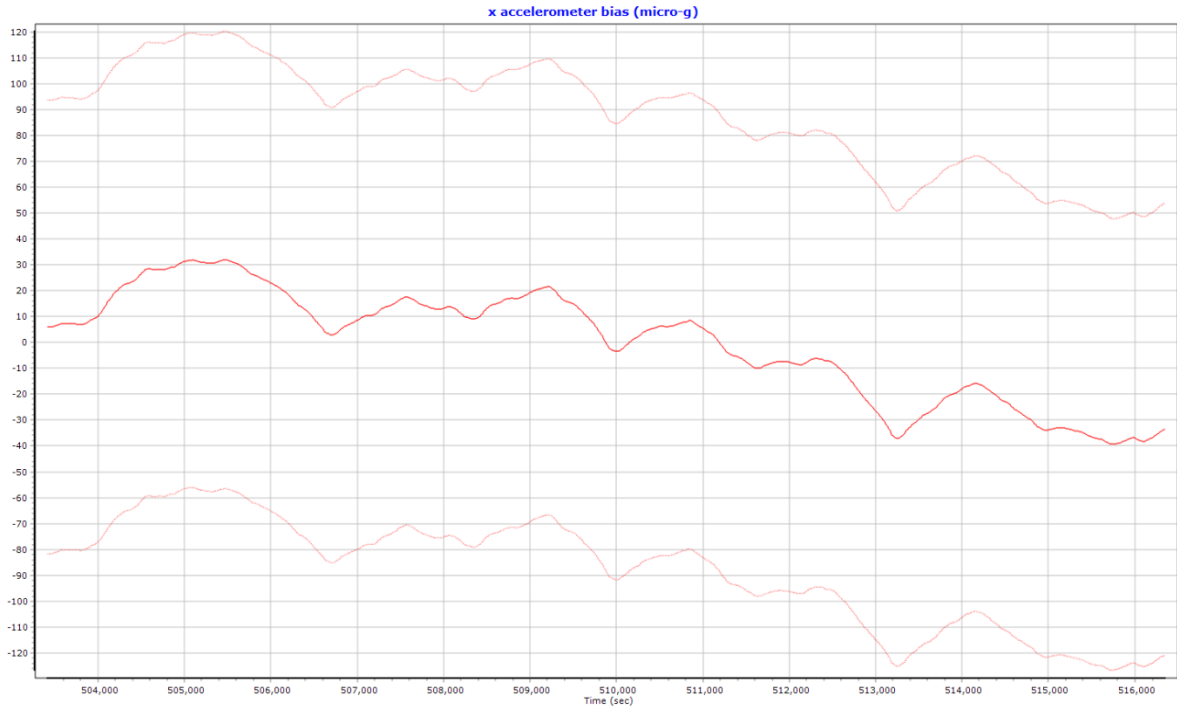
End: 516359.906 Output Record: 0.005000

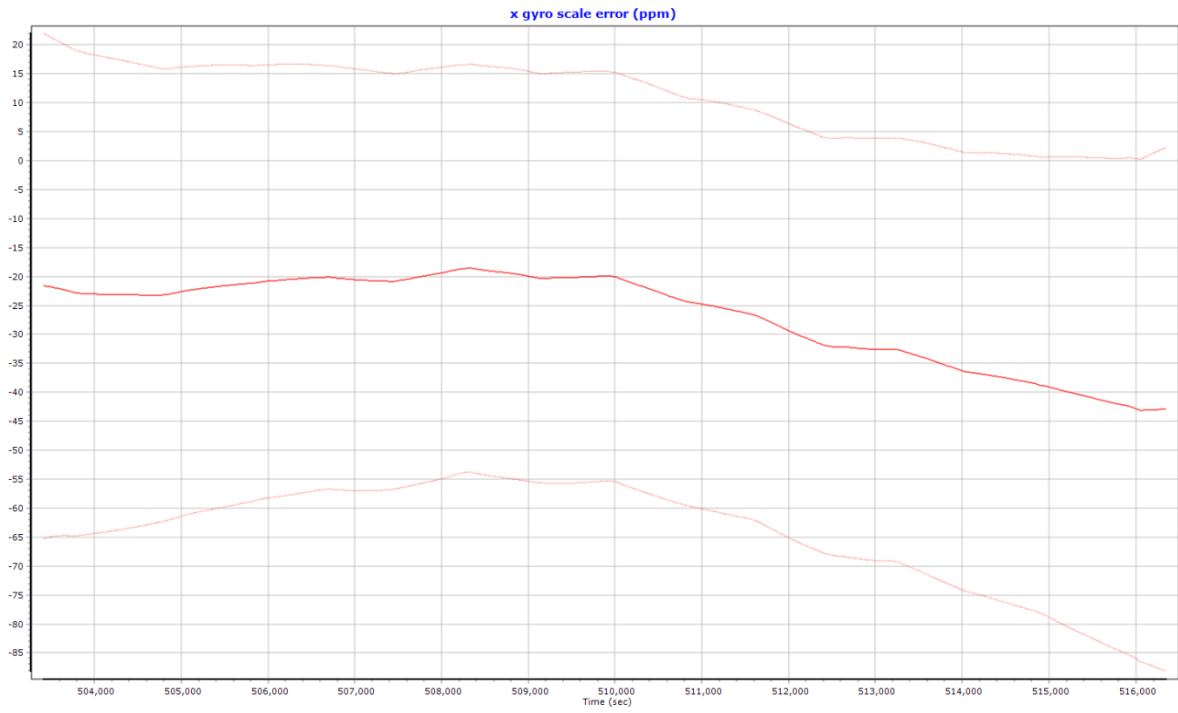
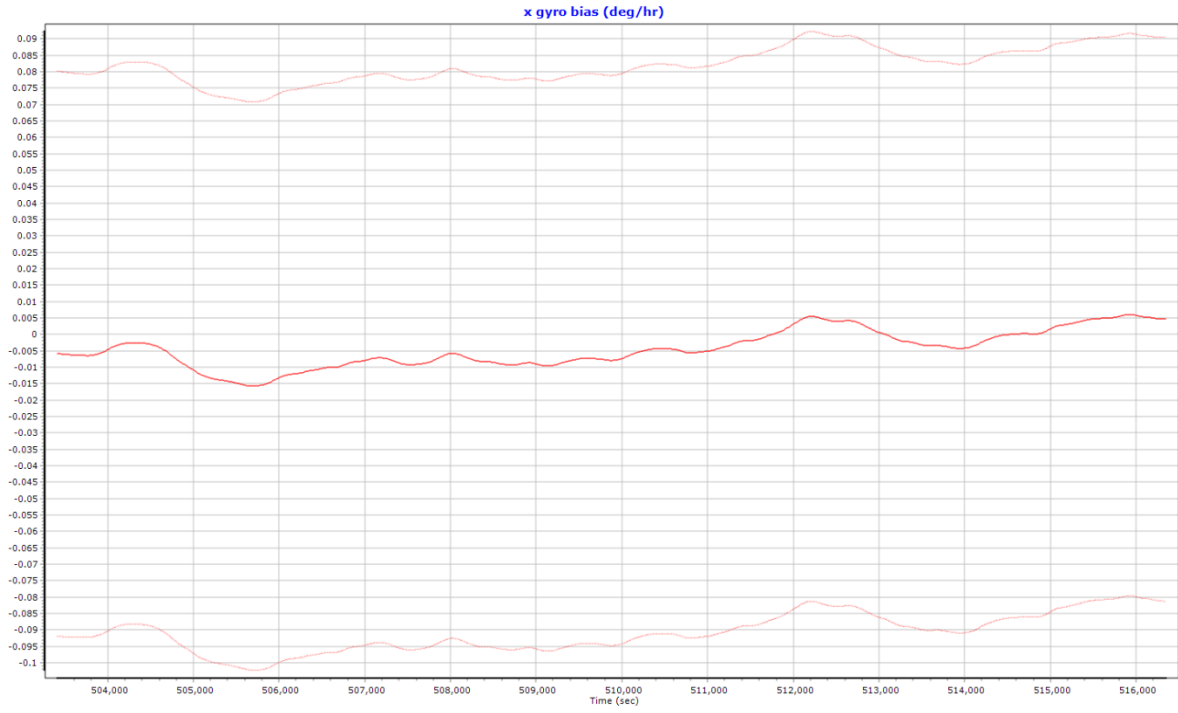
Entire time interval IMU: 0.005000

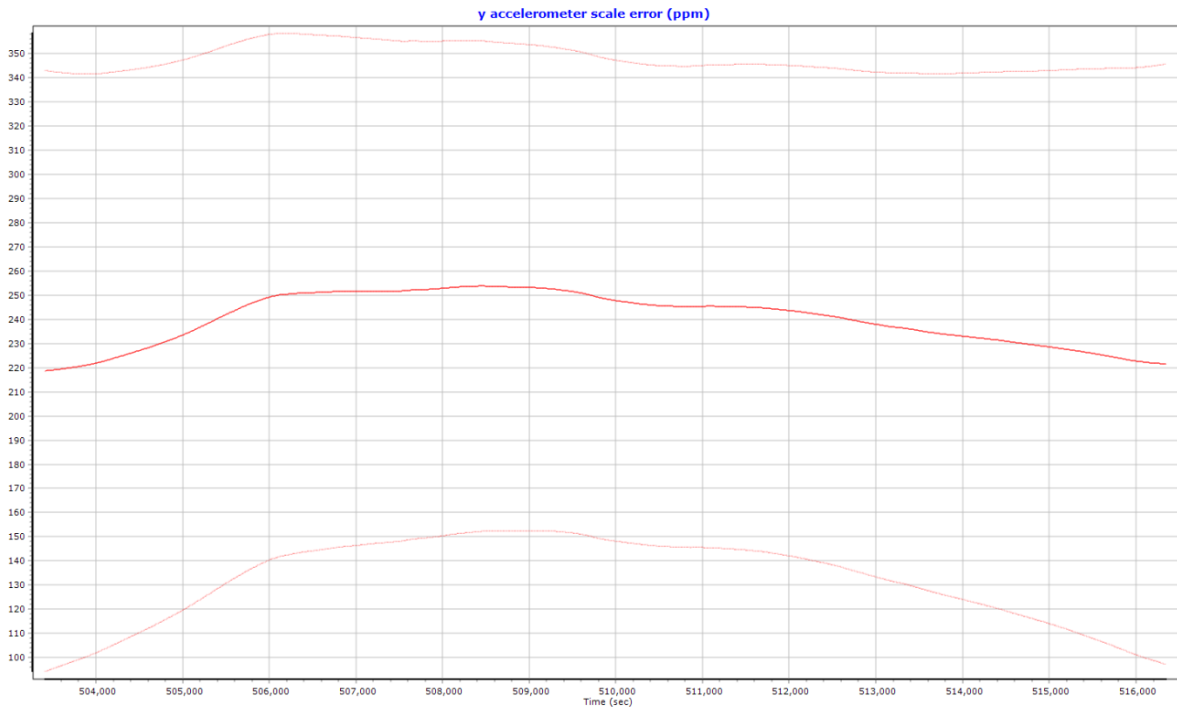
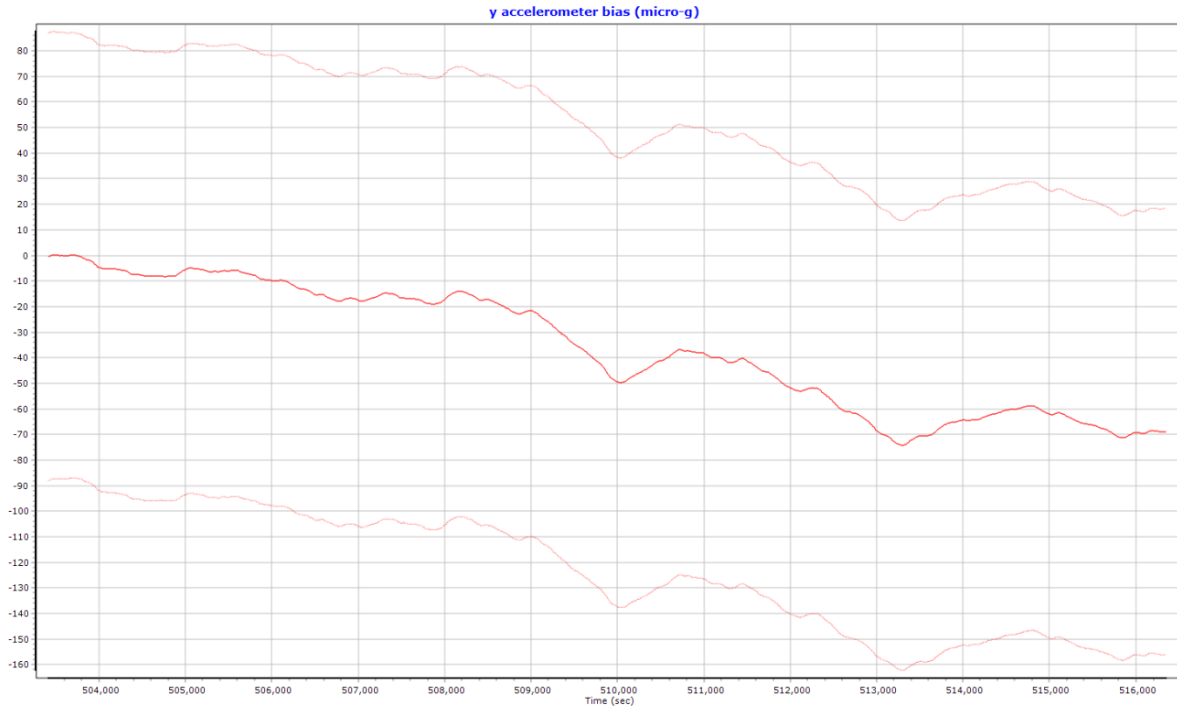
Seconds of start week Primary GNSS: 1.000000 ▼

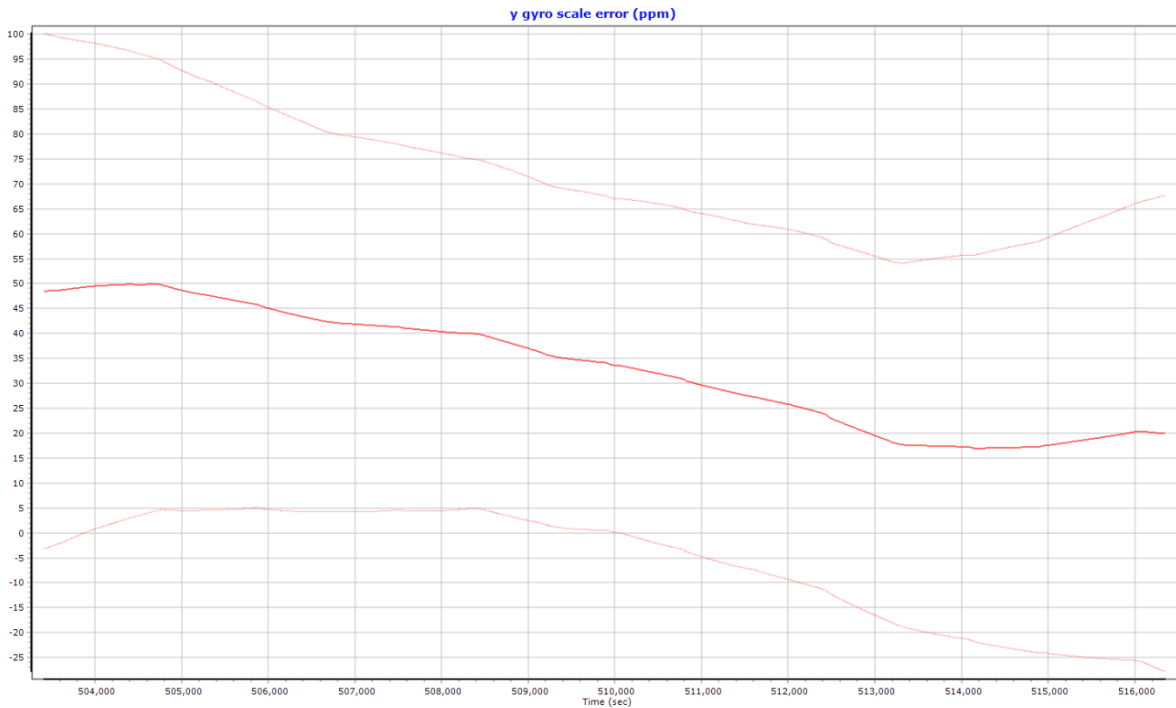
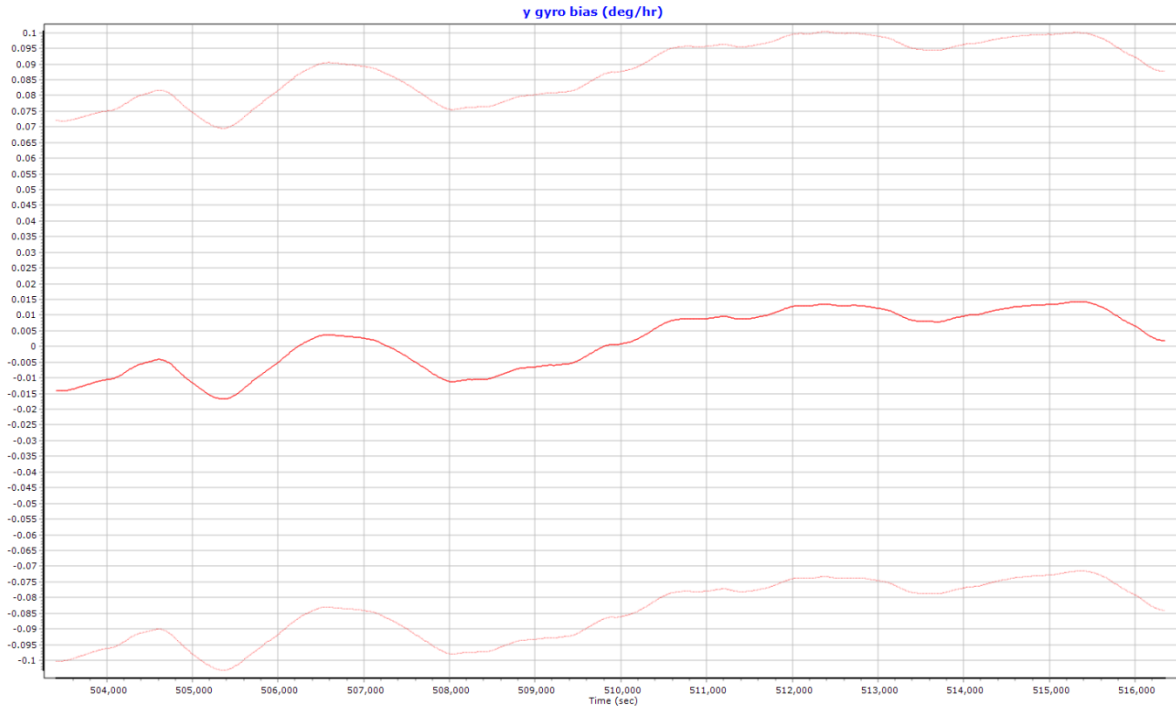
UTC Offset: 18.000

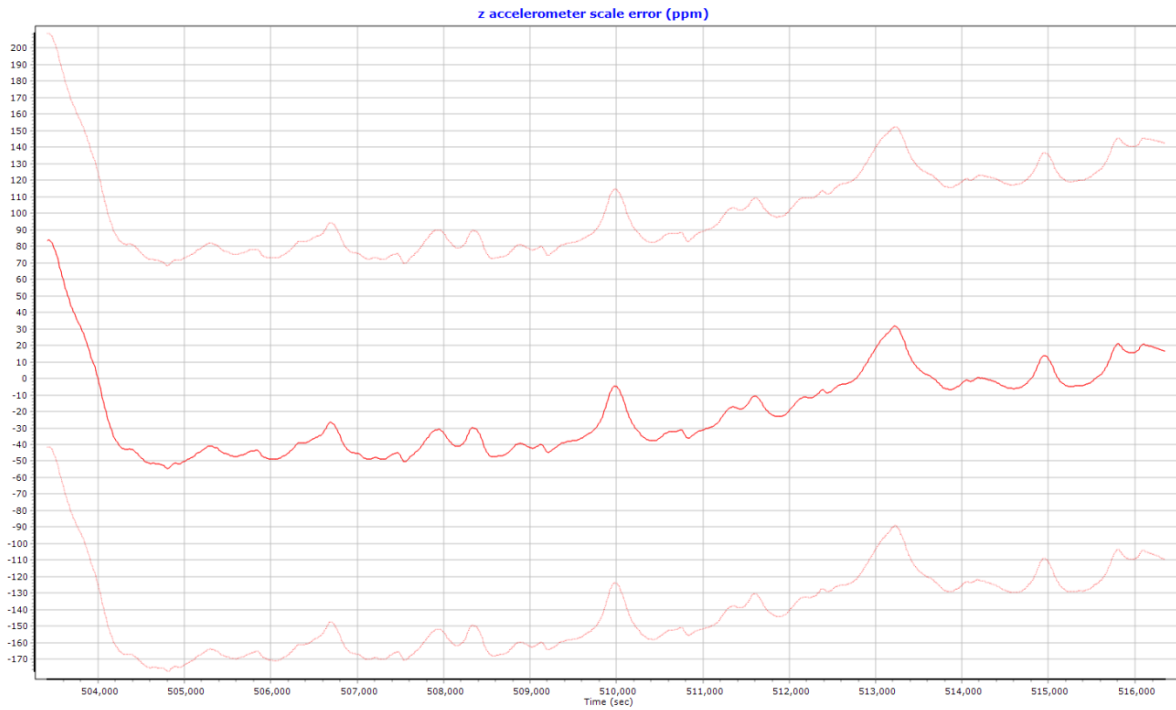
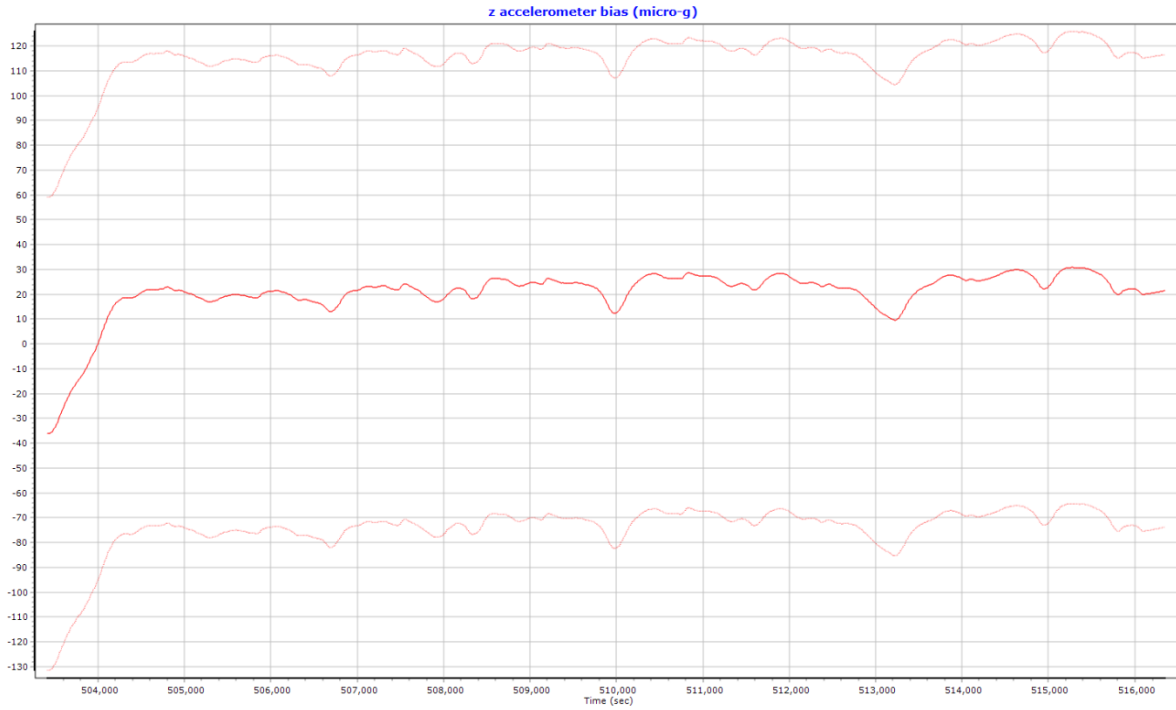
OK Cancel

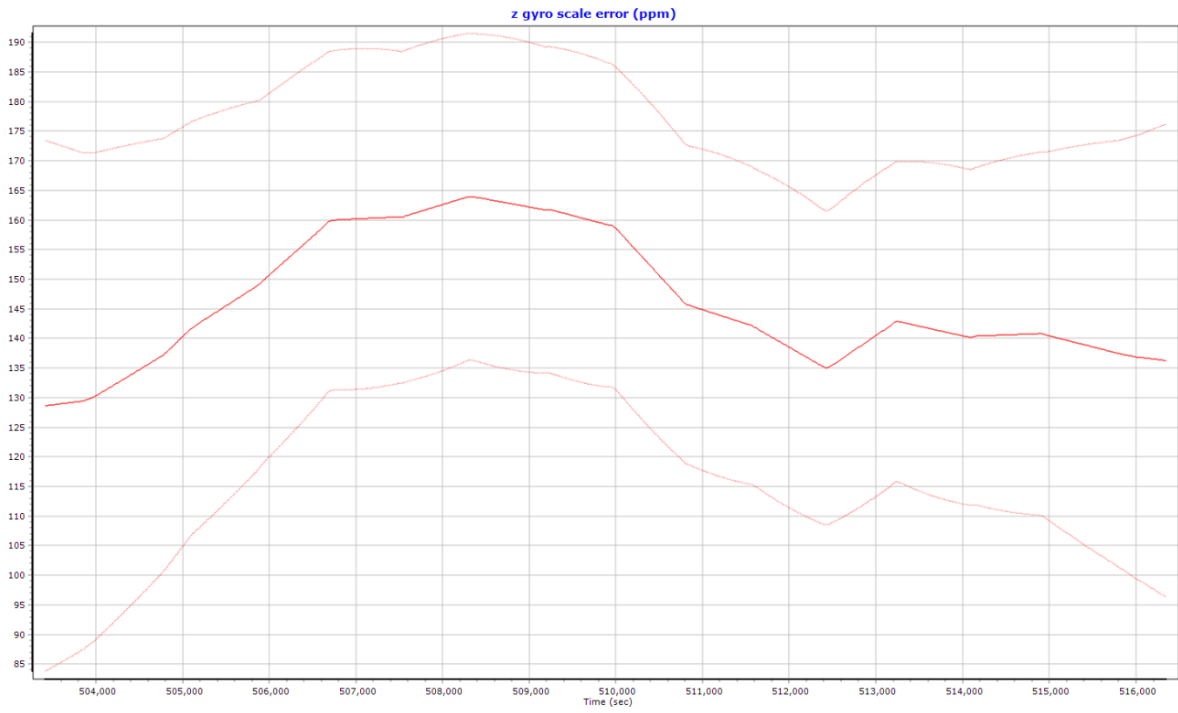
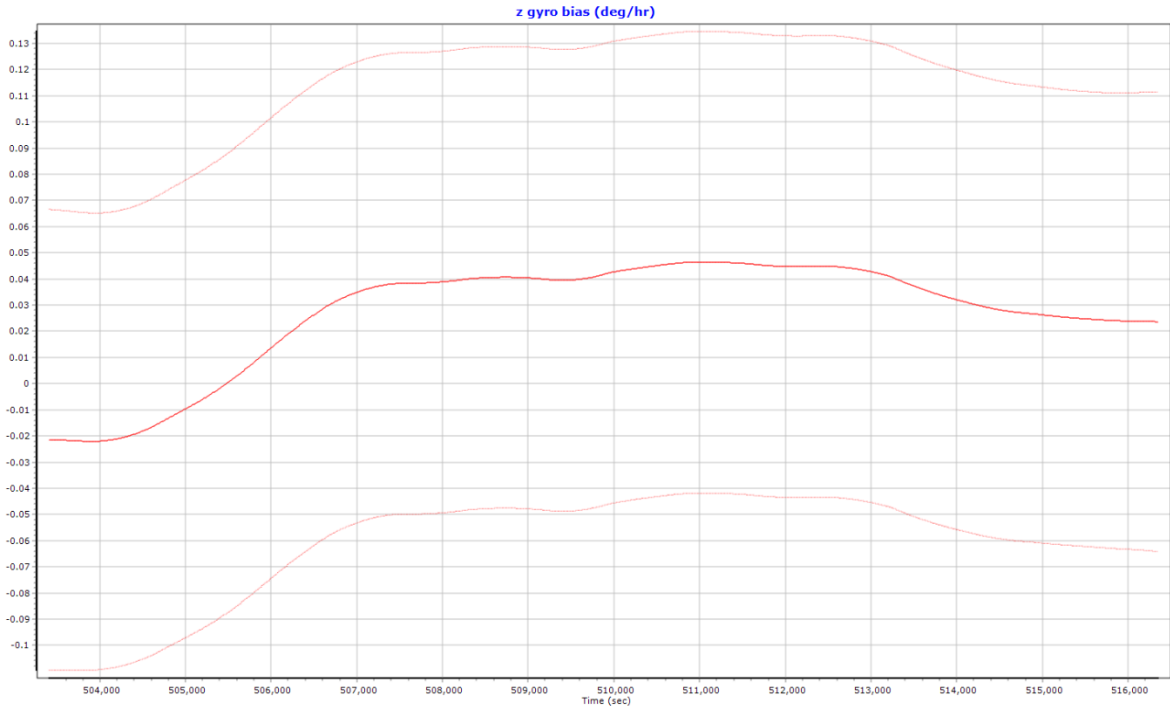




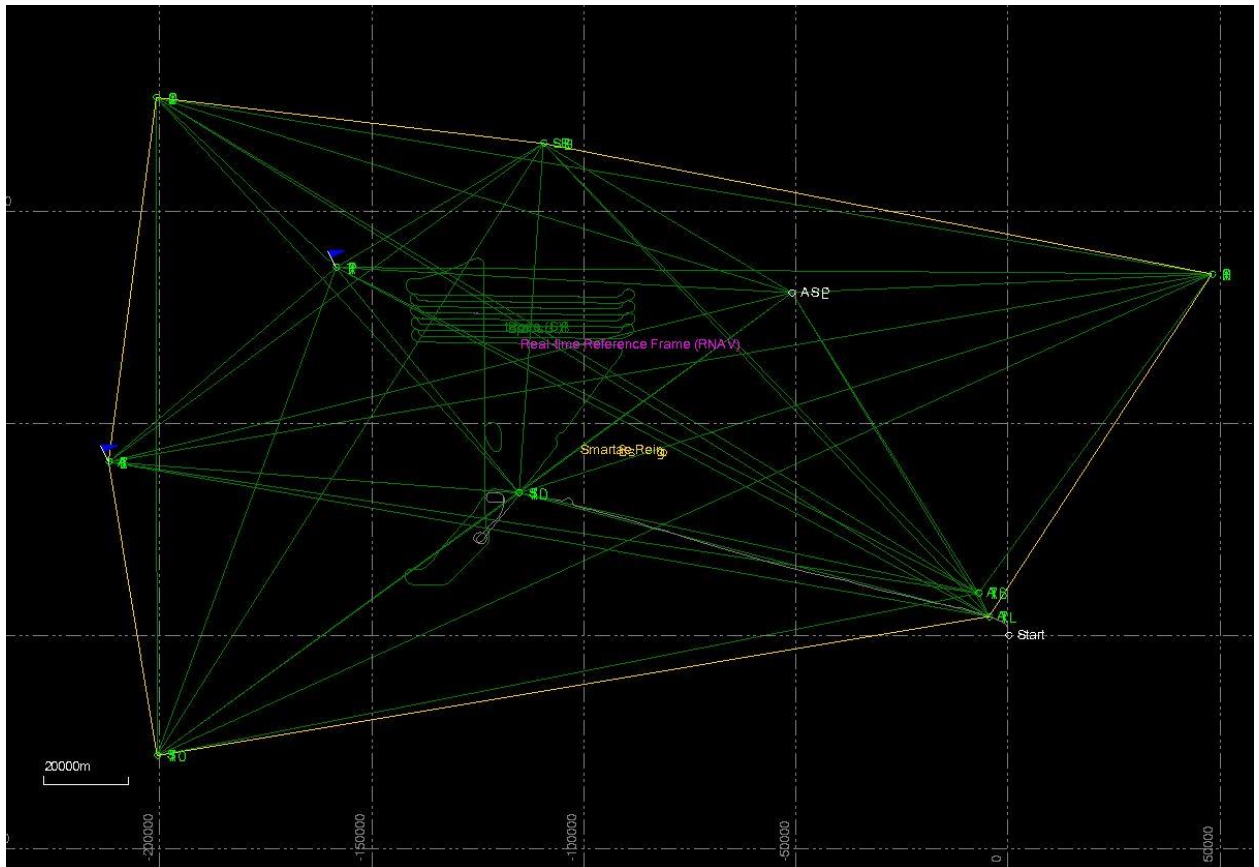
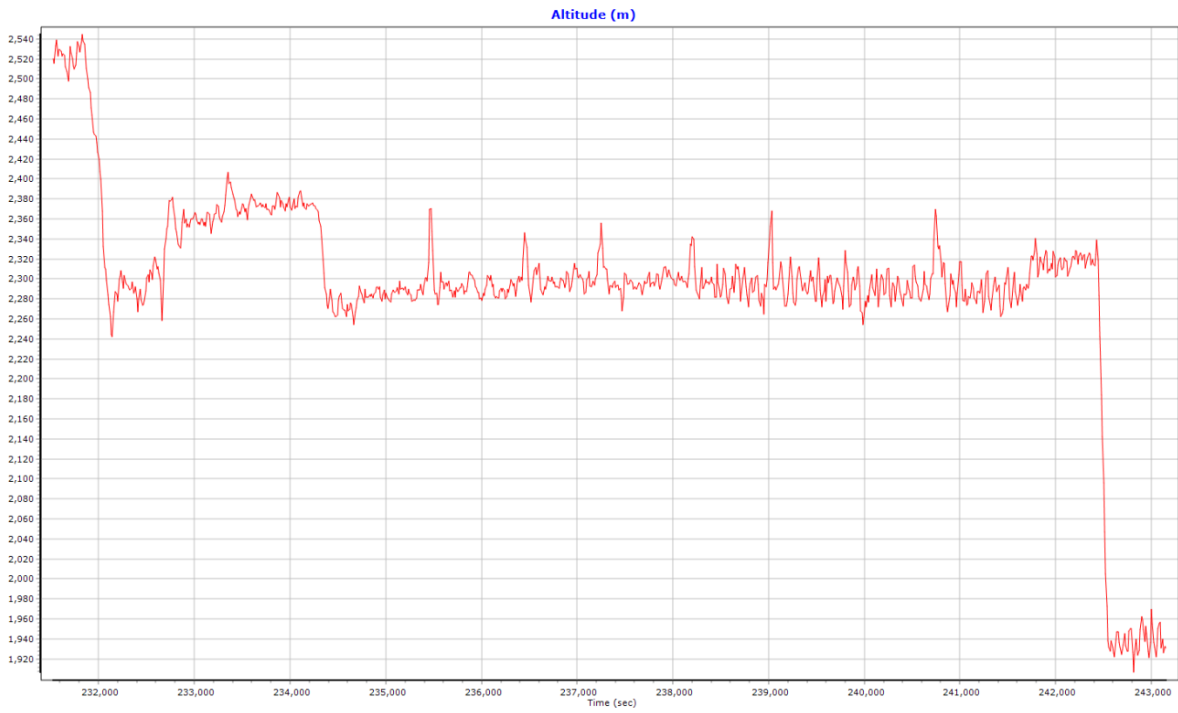








RBV18065A





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:

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

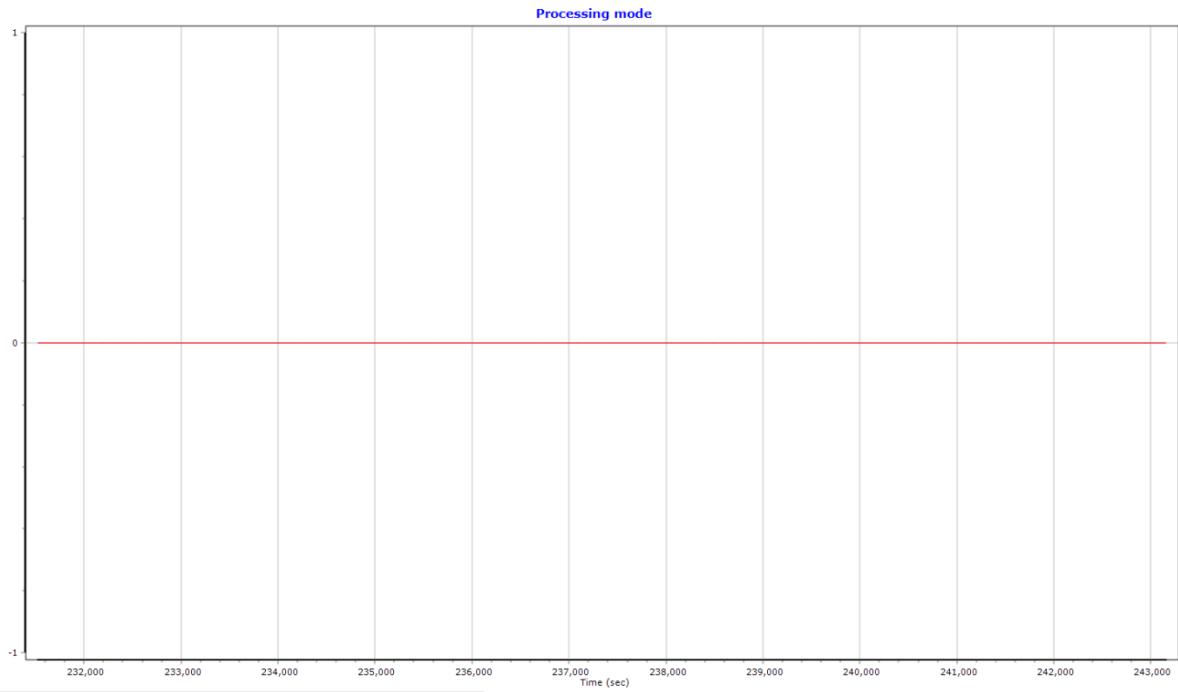
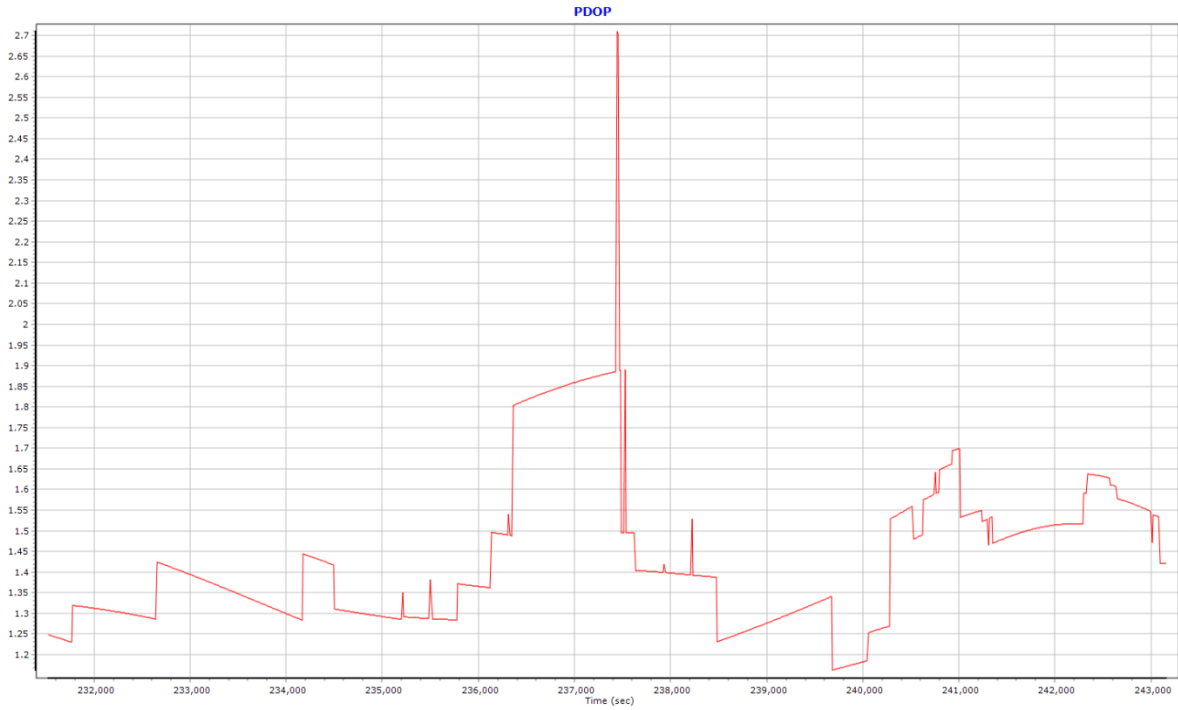
Aircraft to Stabilized Mount Mounting Angles

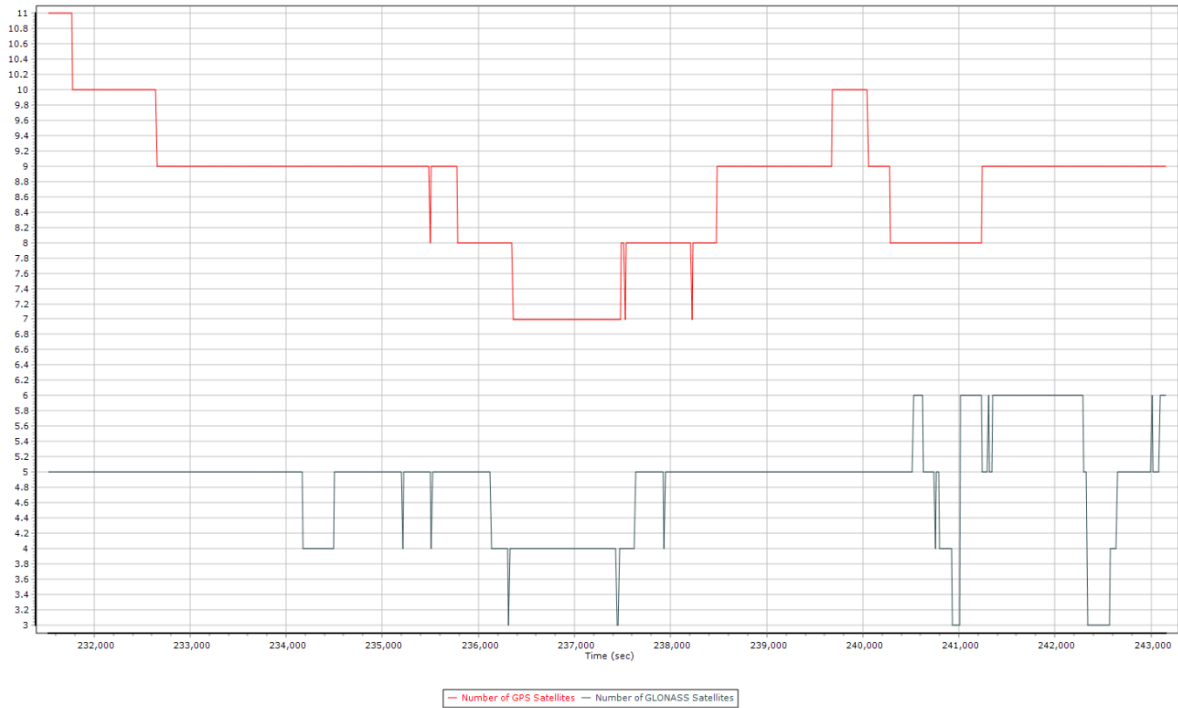
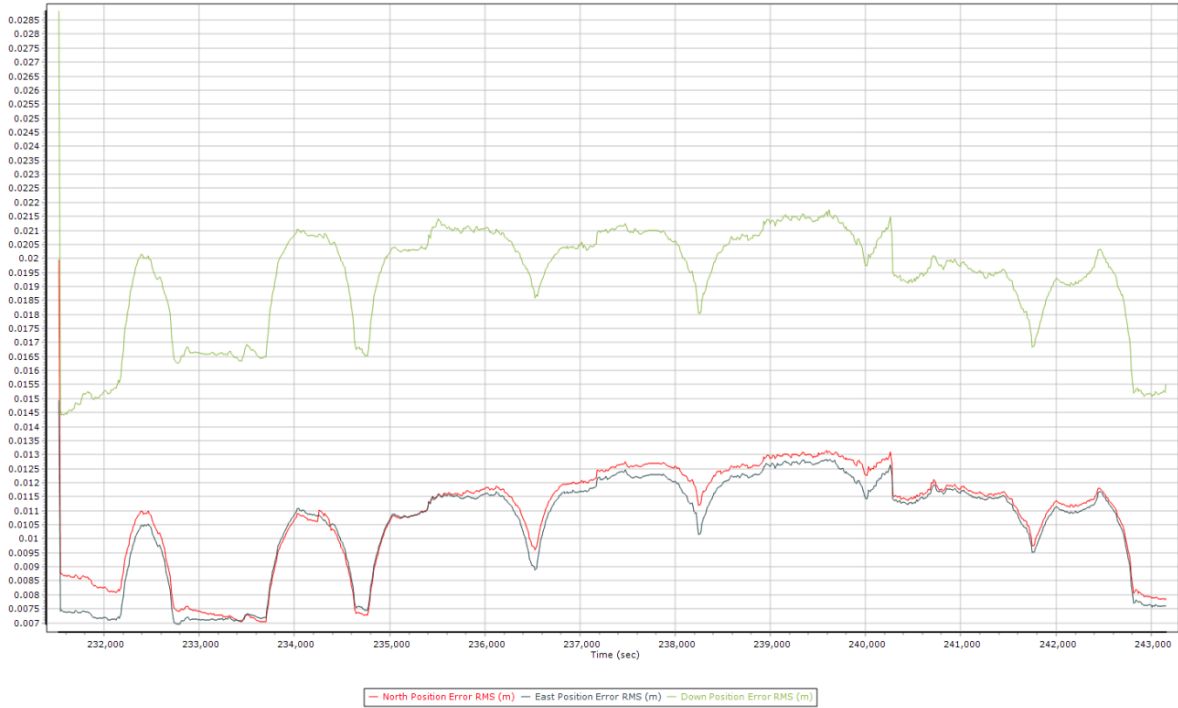
X:

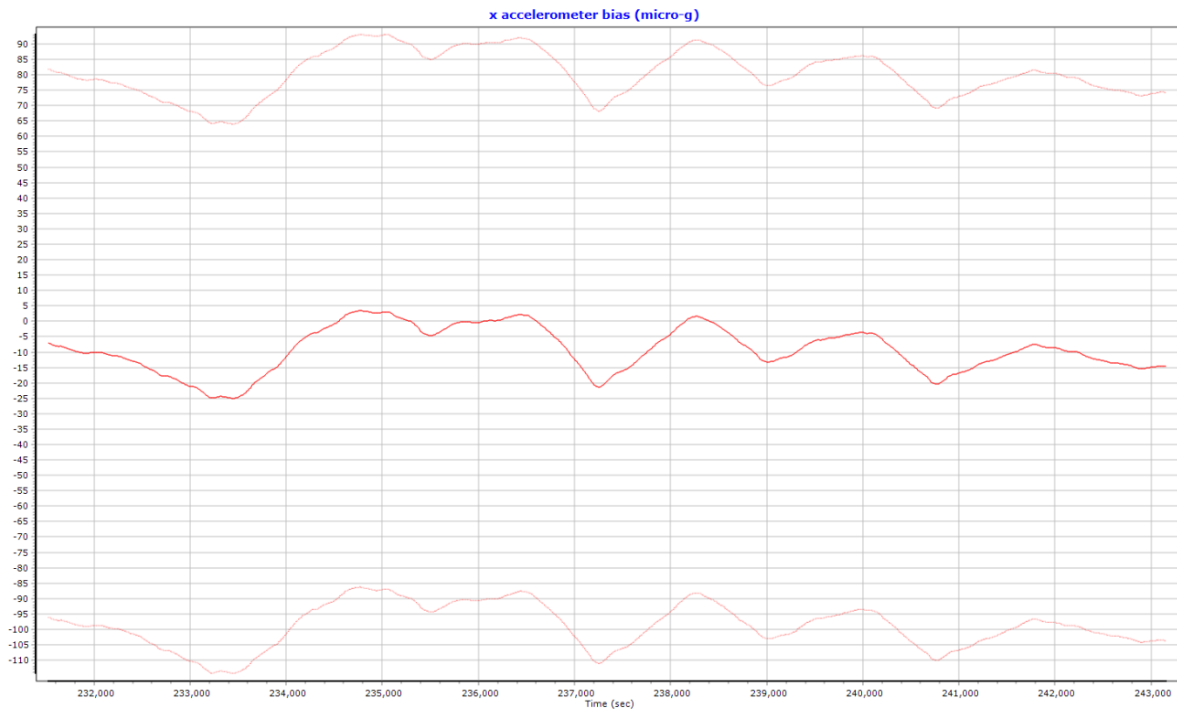
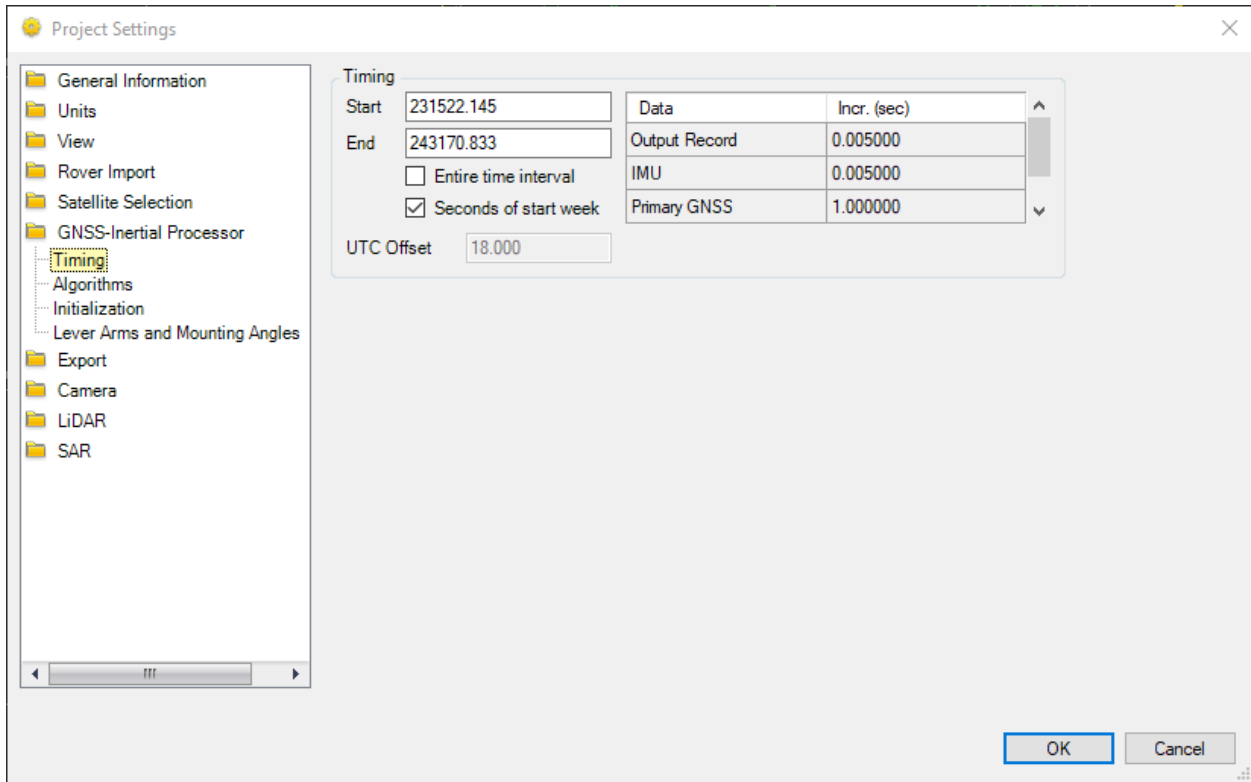
Y:

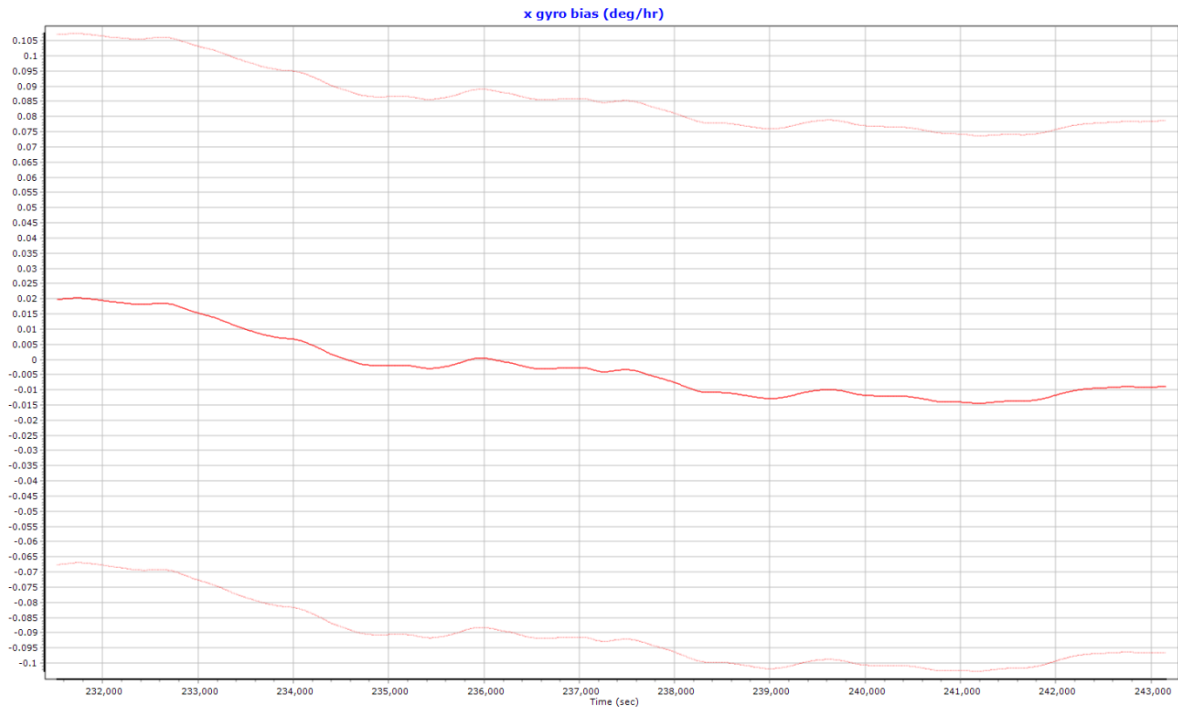
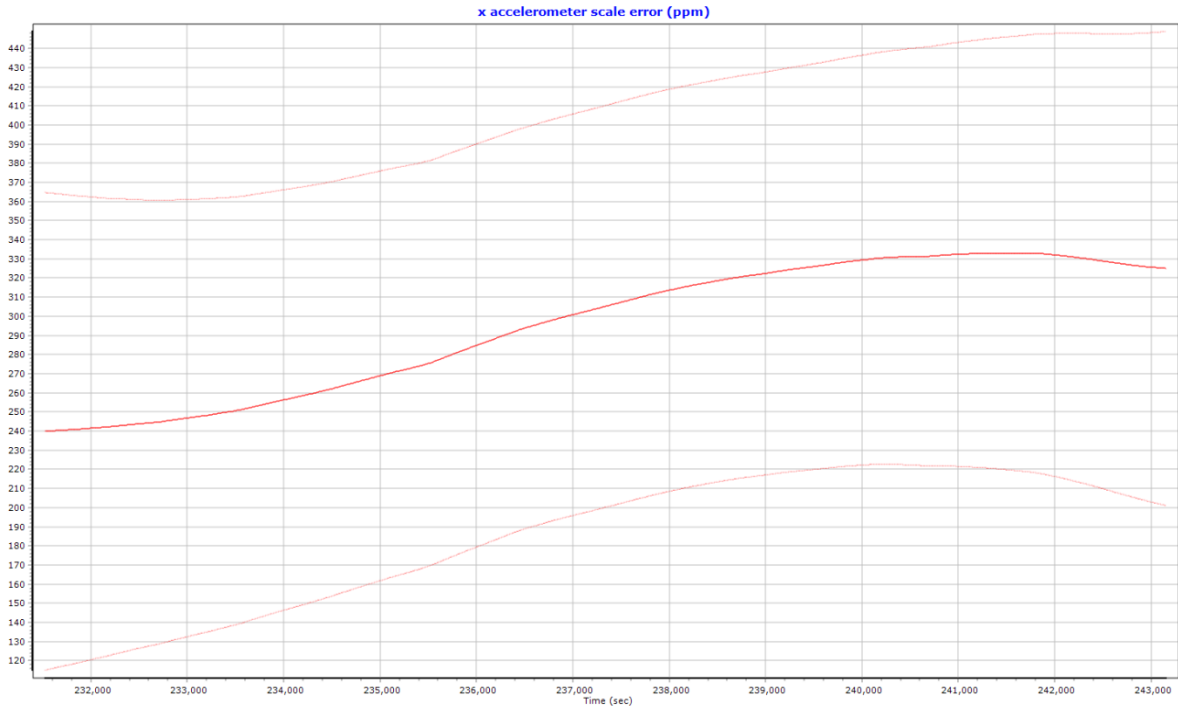
Z:

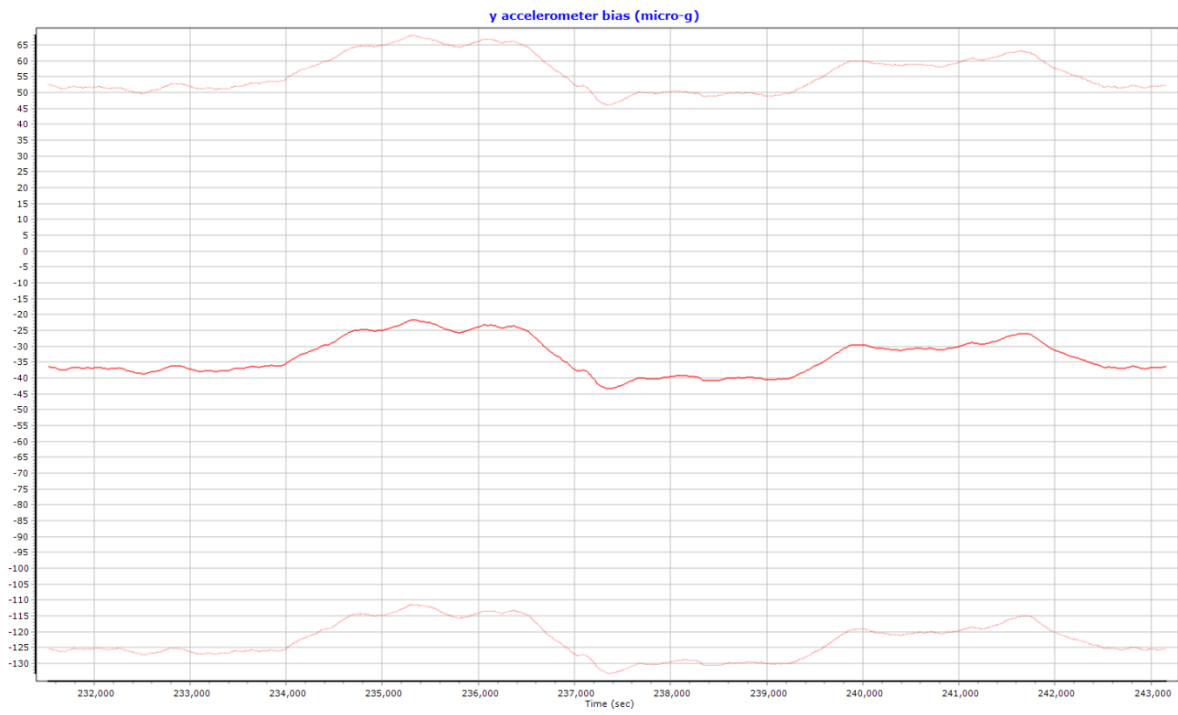
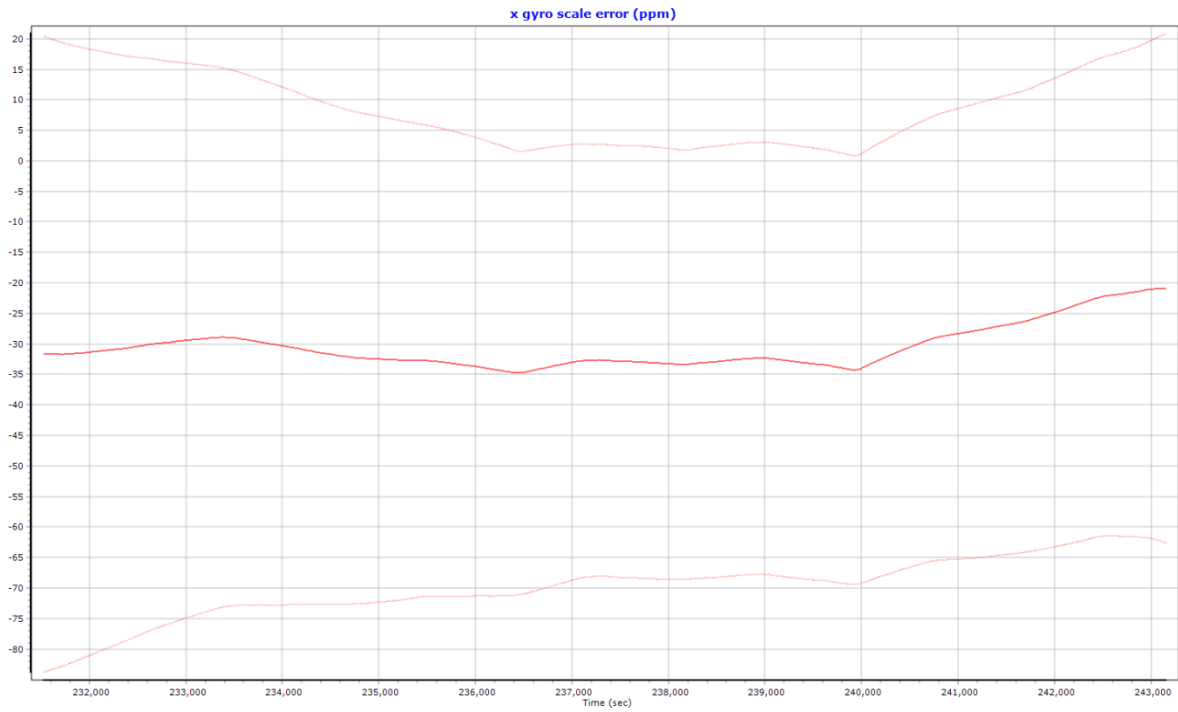
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

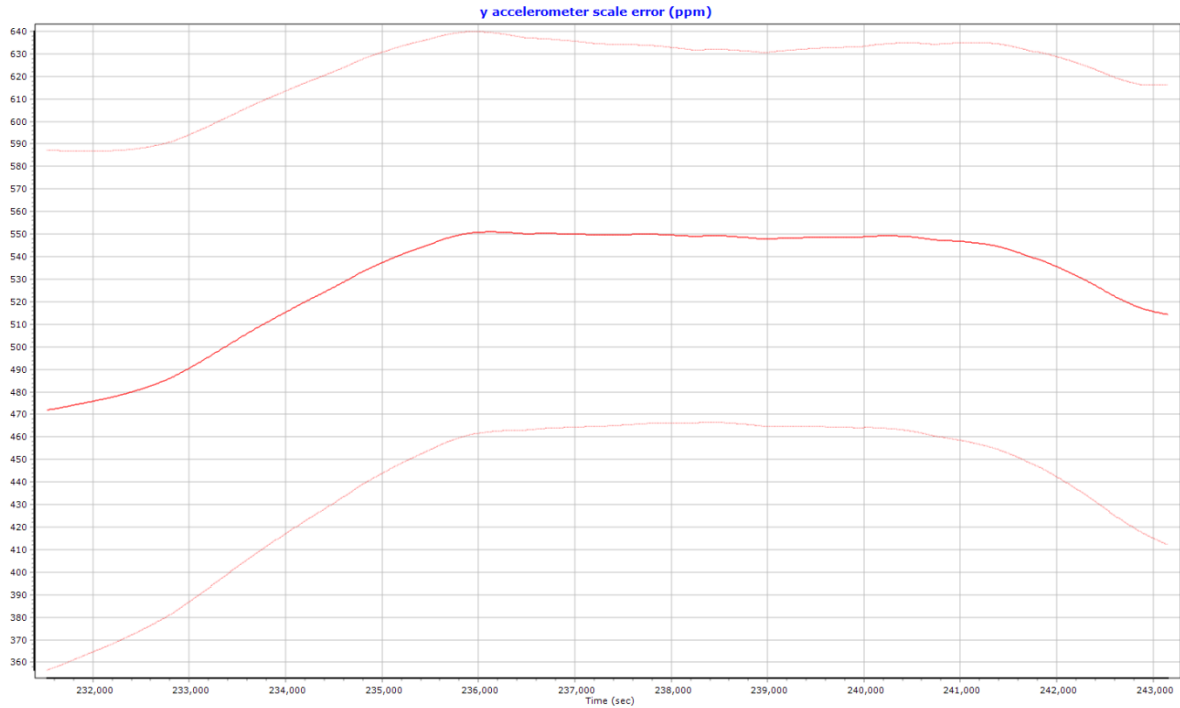


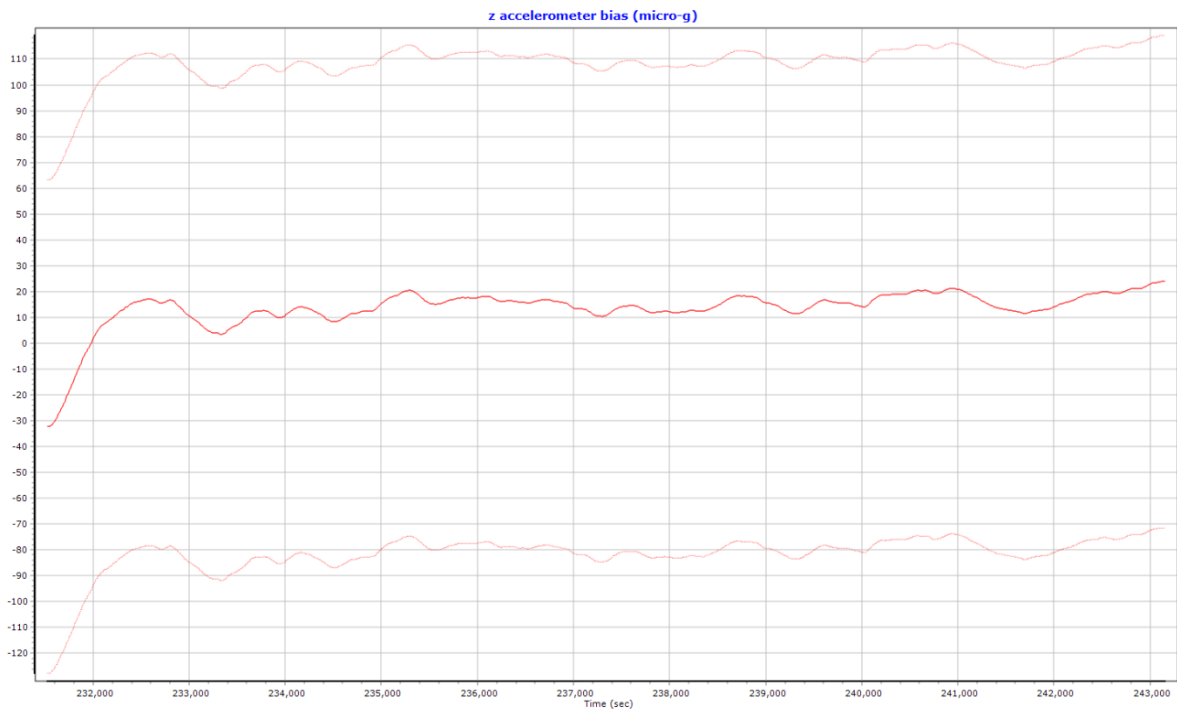
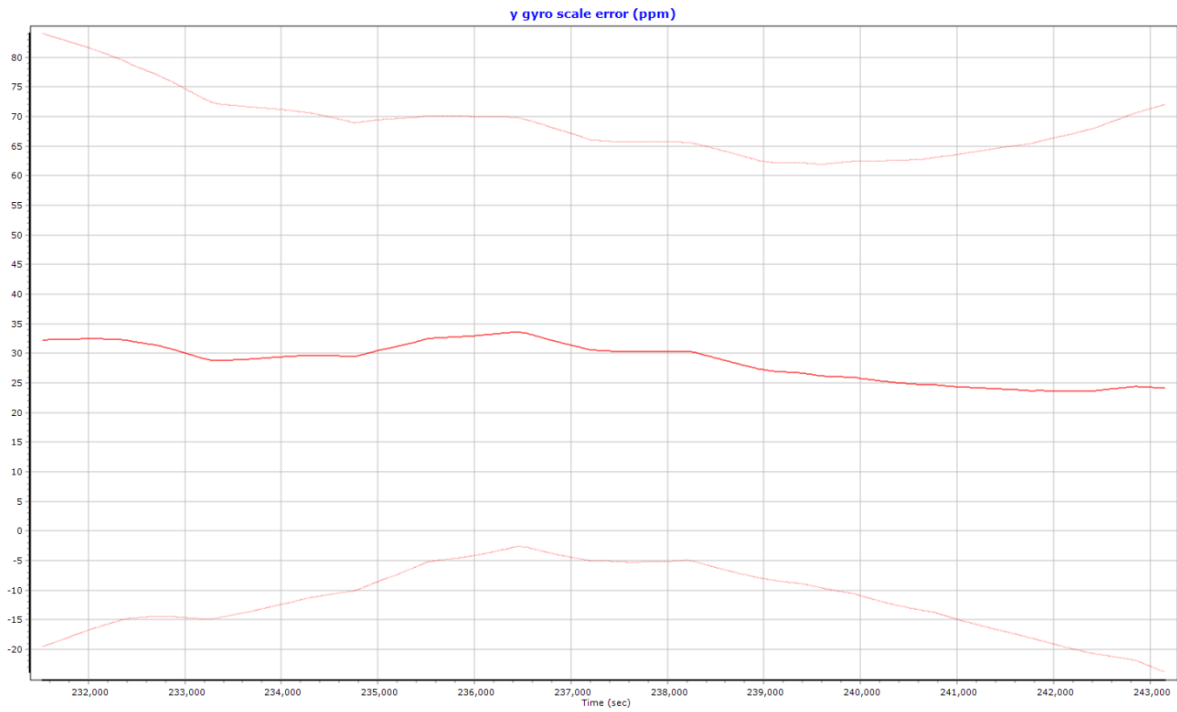


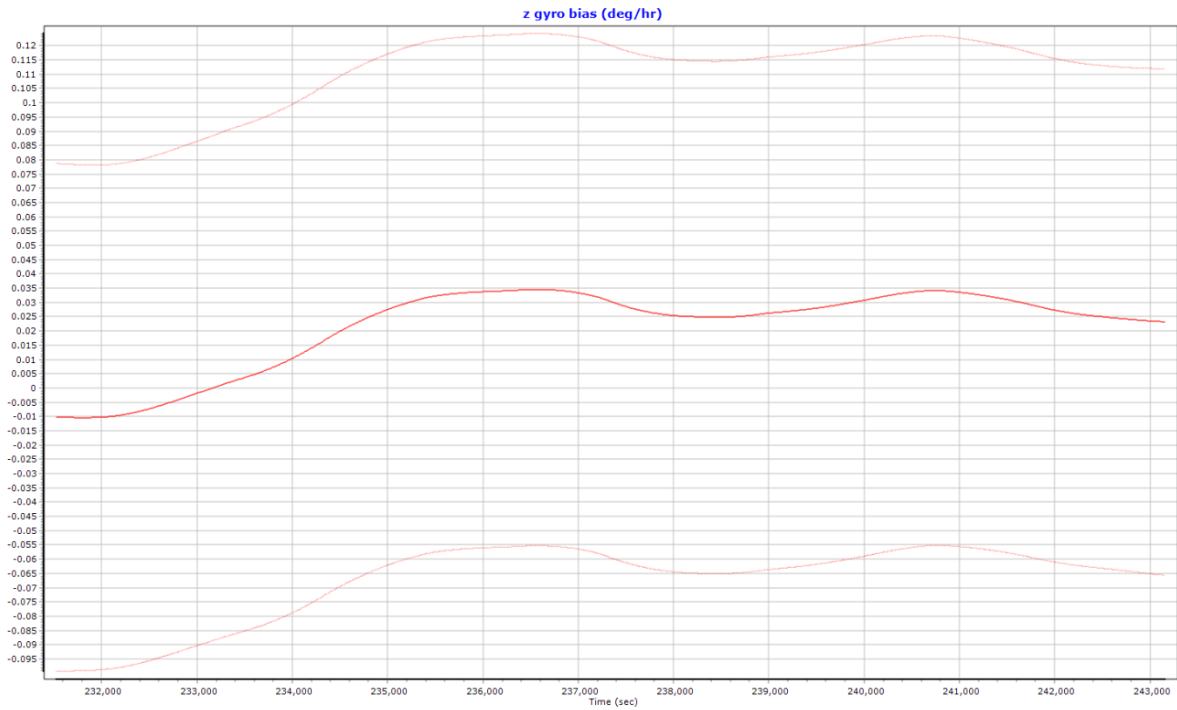
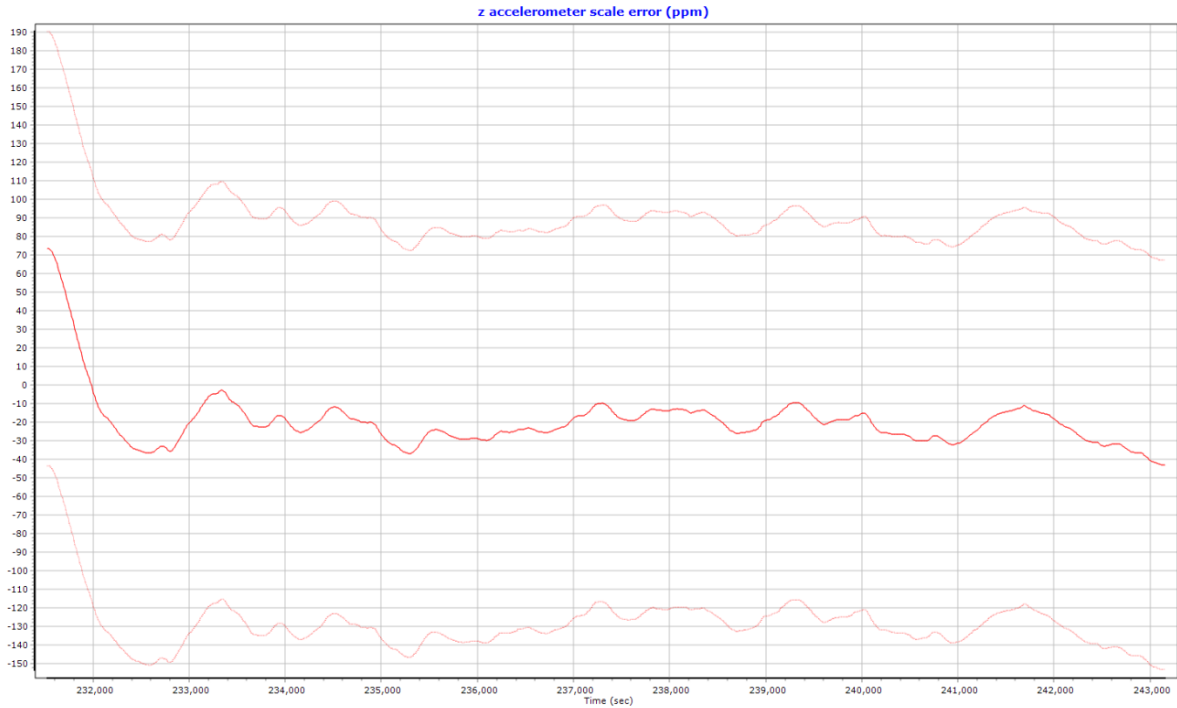


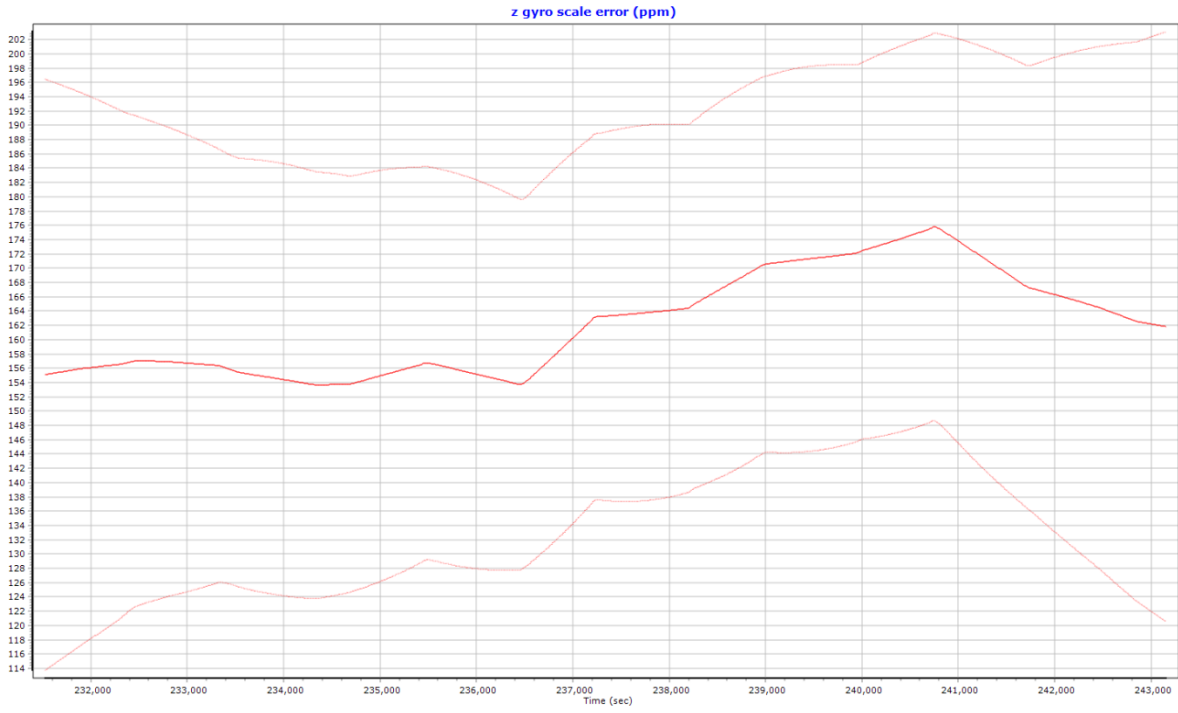




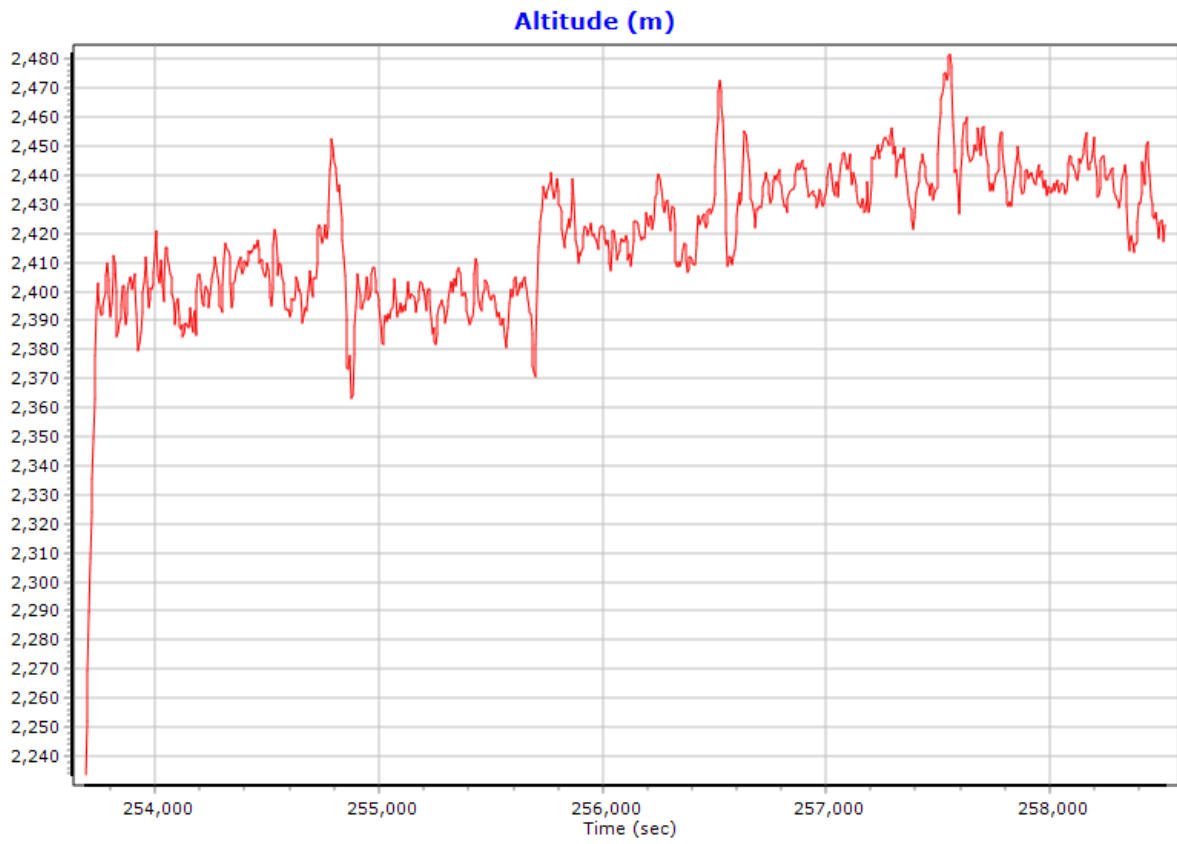


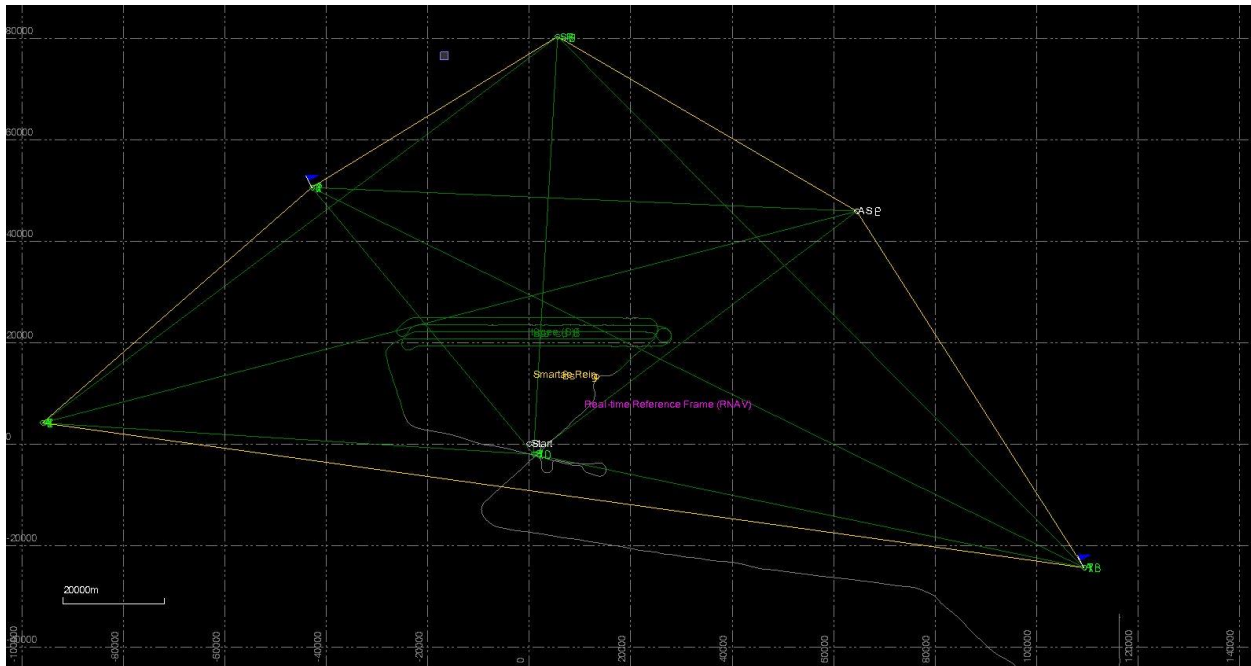
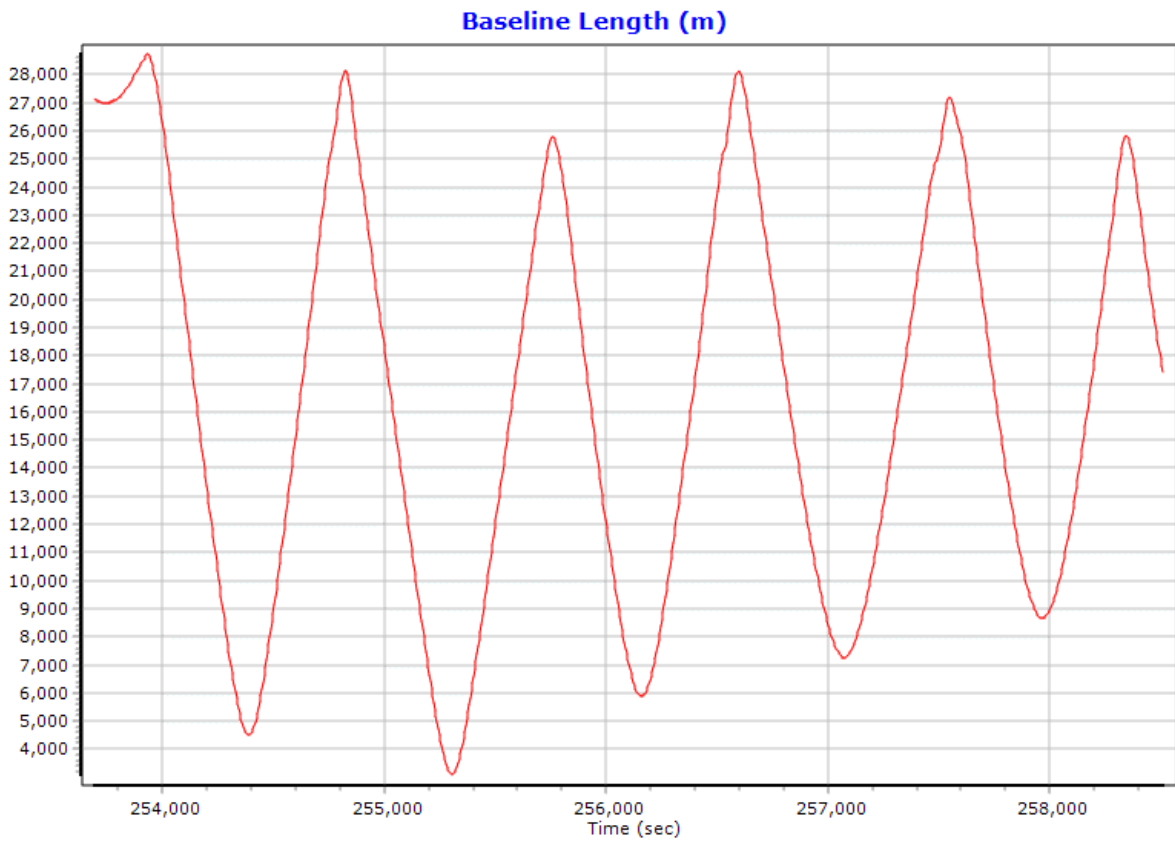


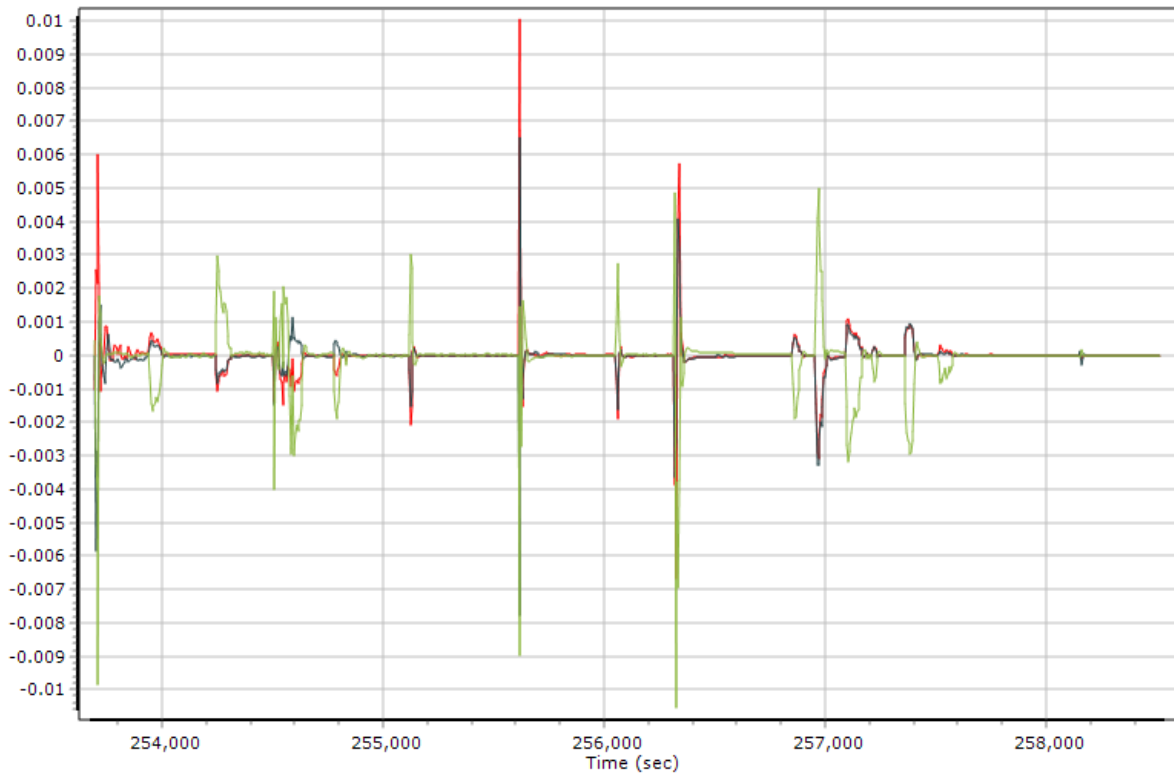




RBV18065B







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 Primary GNSS Lever Arm

X: -0.031 m

Y: 0.004 m

Z: -0.611 m

Standard Deviation

<3cm 10cm 50cm 1m 10m

Reference to IMU Mounting Angles

X: 0.000 deg

Y: 0.000 deg

Z: 0.000 deg

Aircraft to Reference Mounting Angles

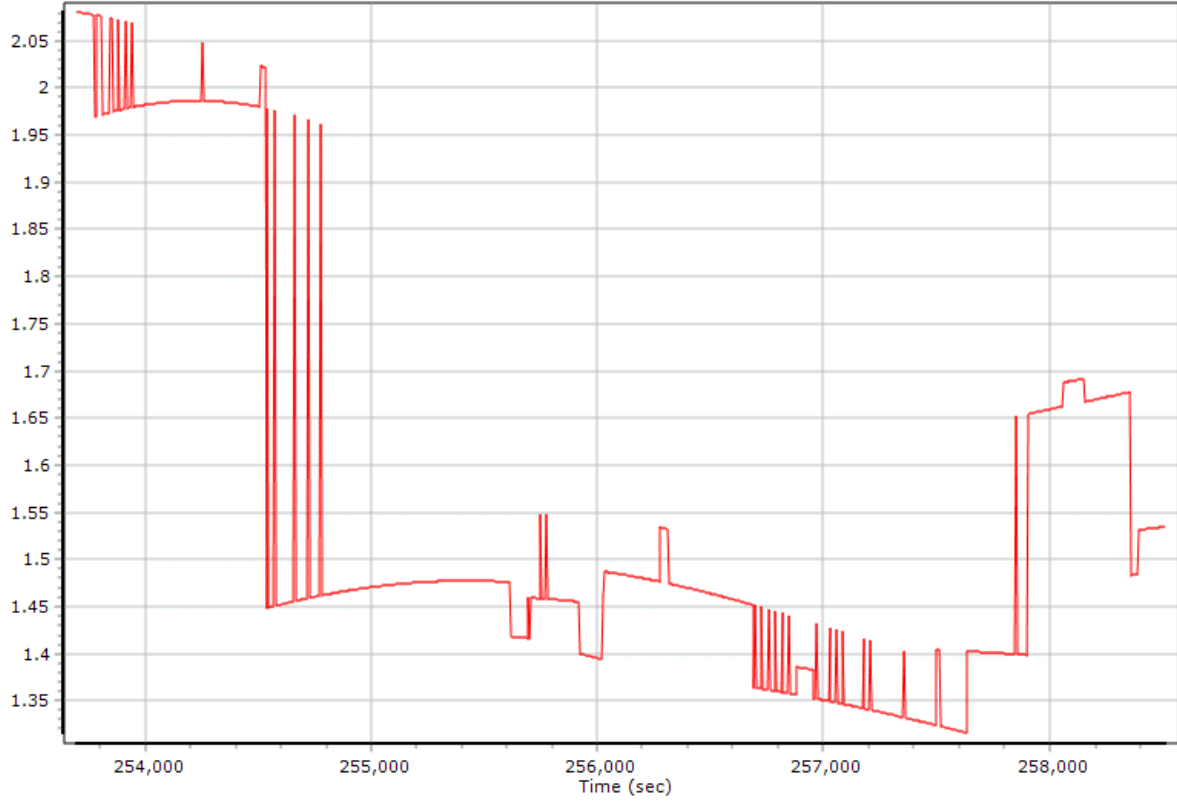
X: 0.000 deg

Y: 0.000 deg

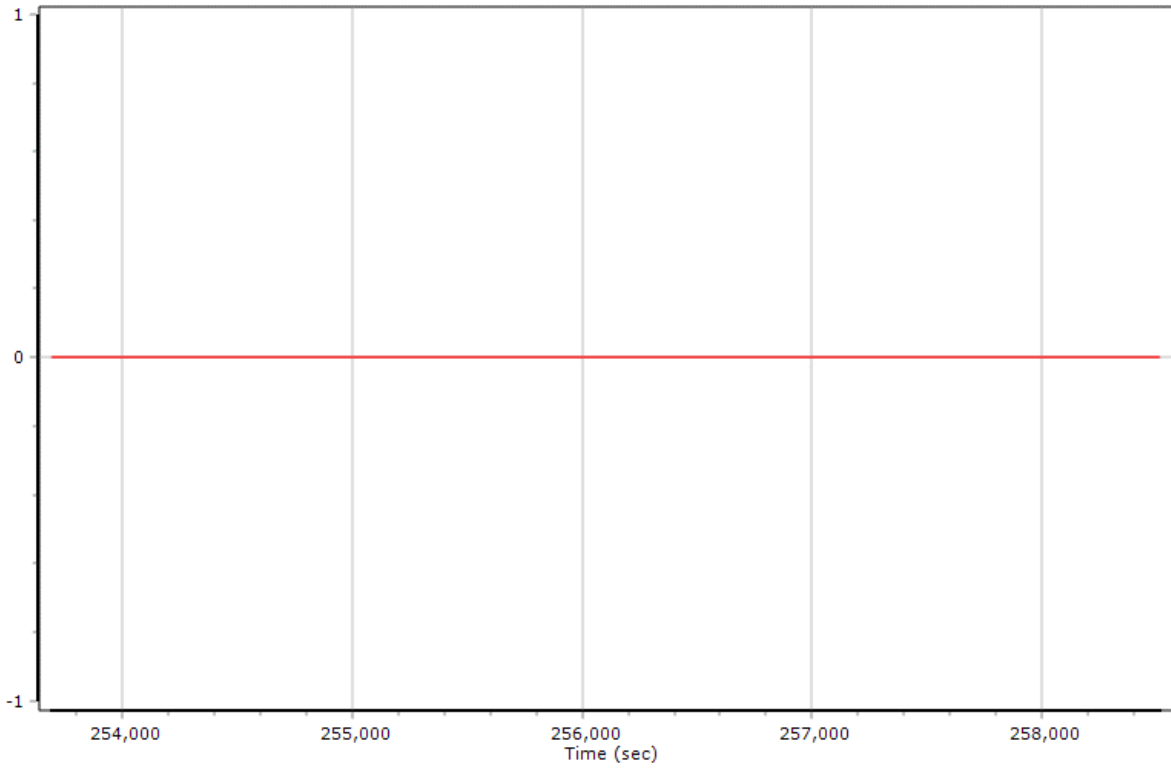
Z: 0.000 deg

OK Cancel

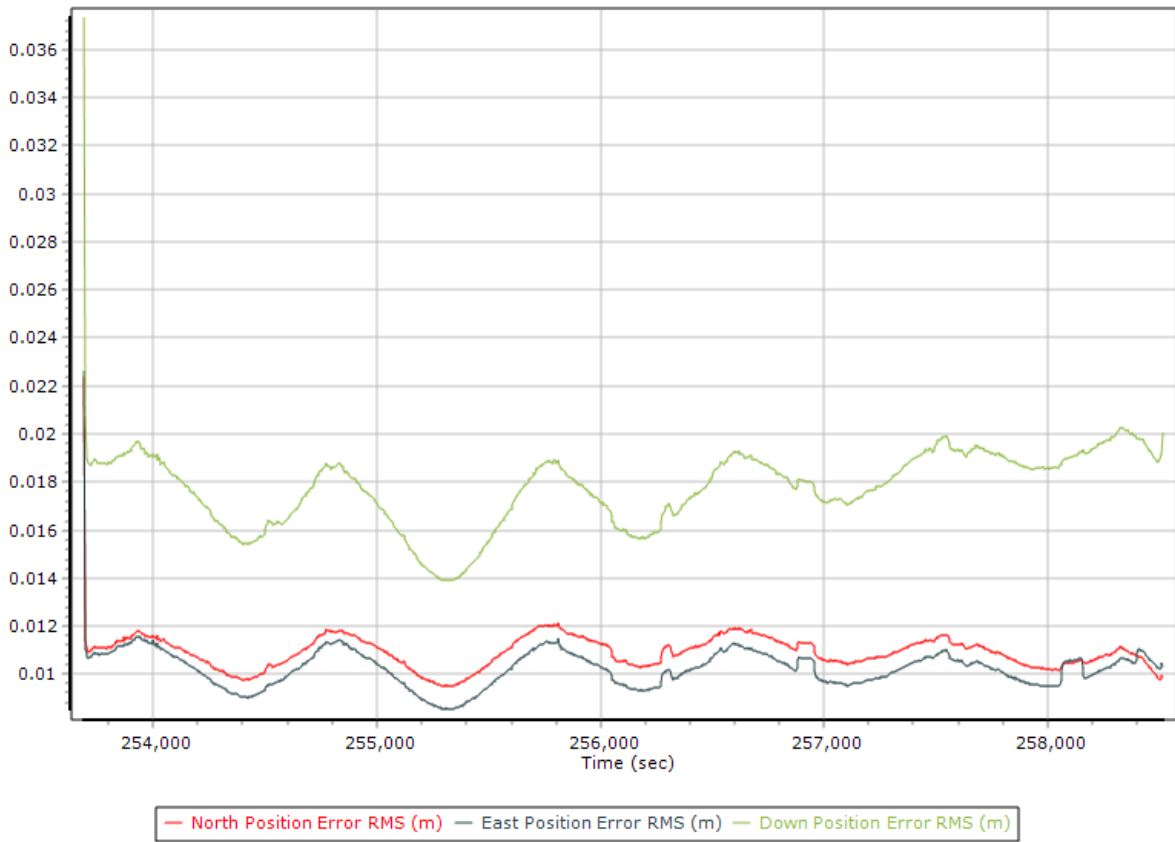
PDOP

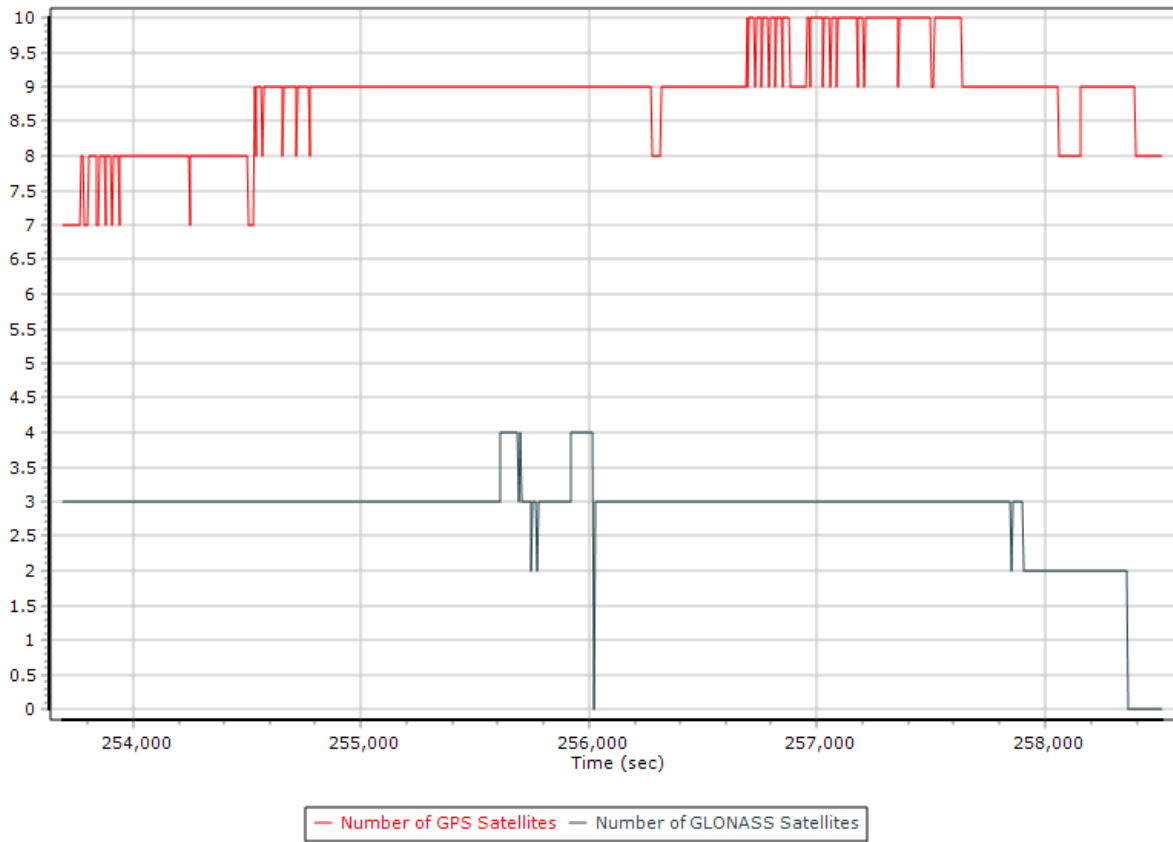


Processing mode



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





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

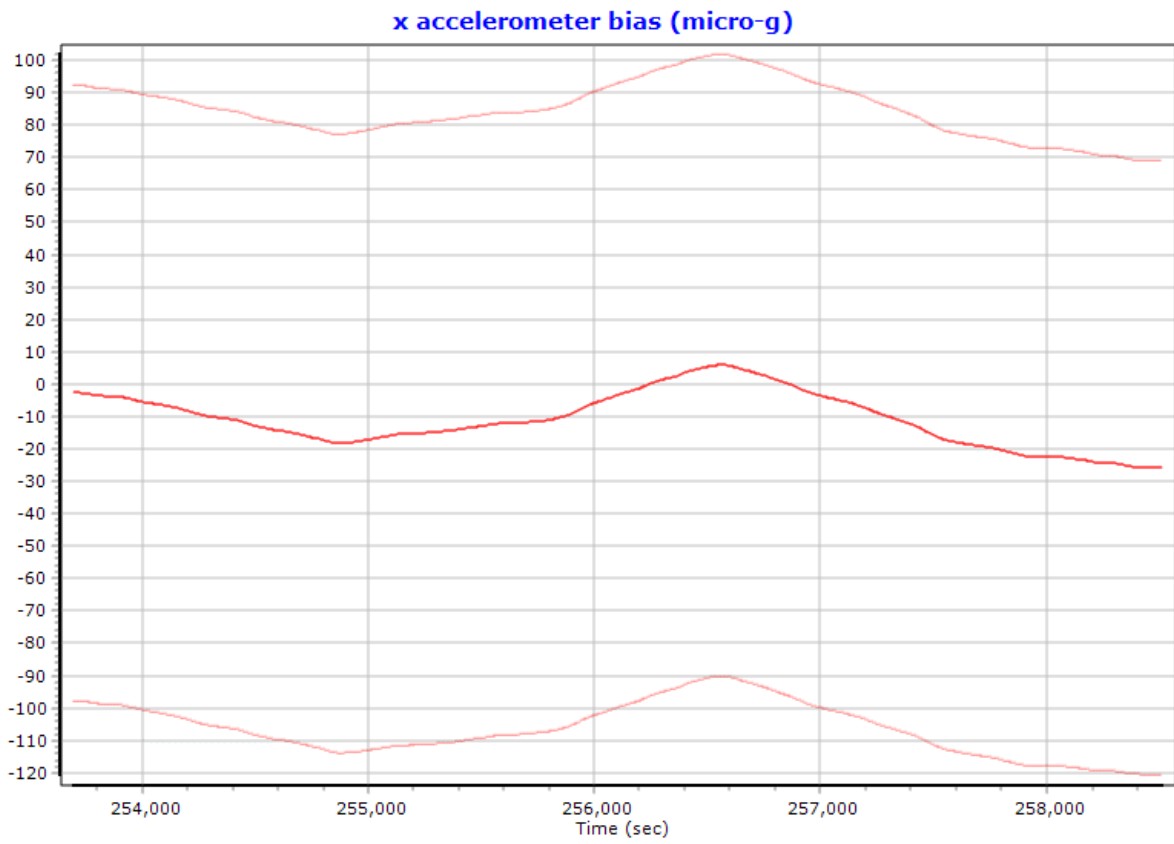
Start: 253690.556
 End: 258520.677

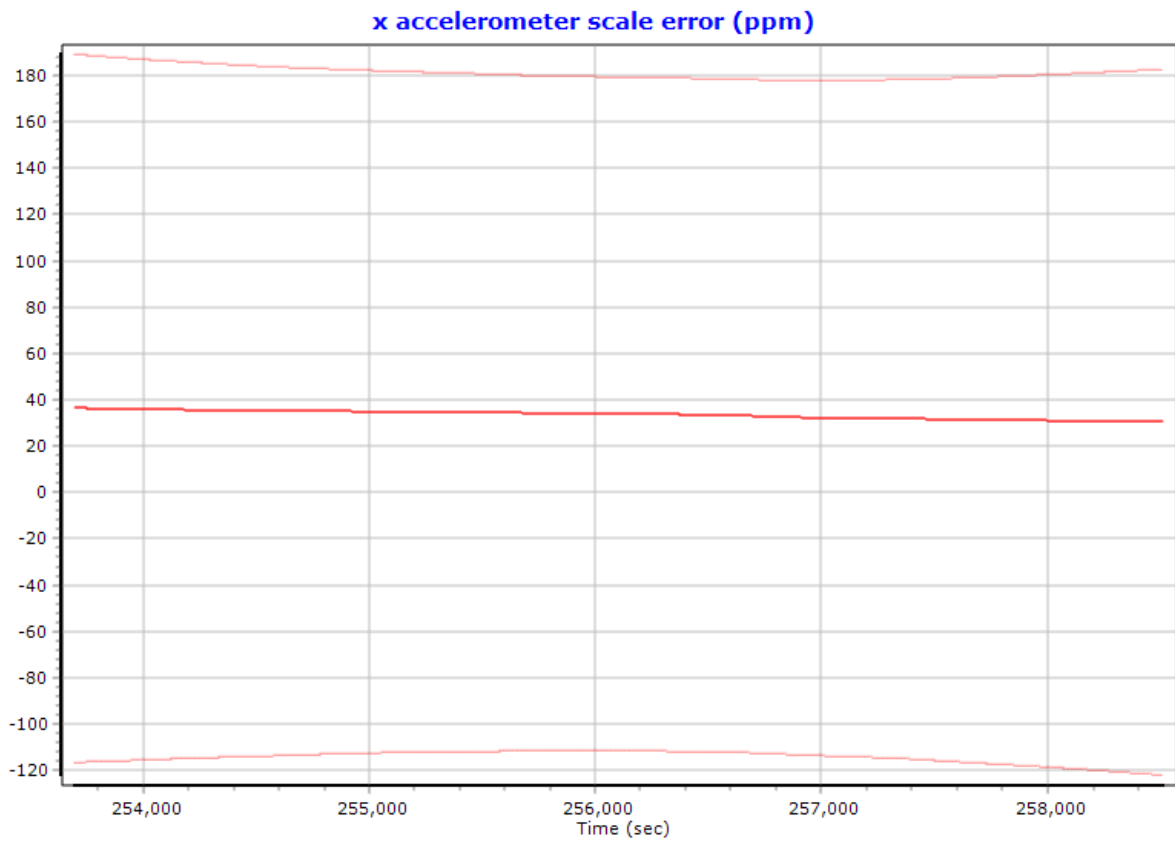
Entire time interval
 Seconds of start week

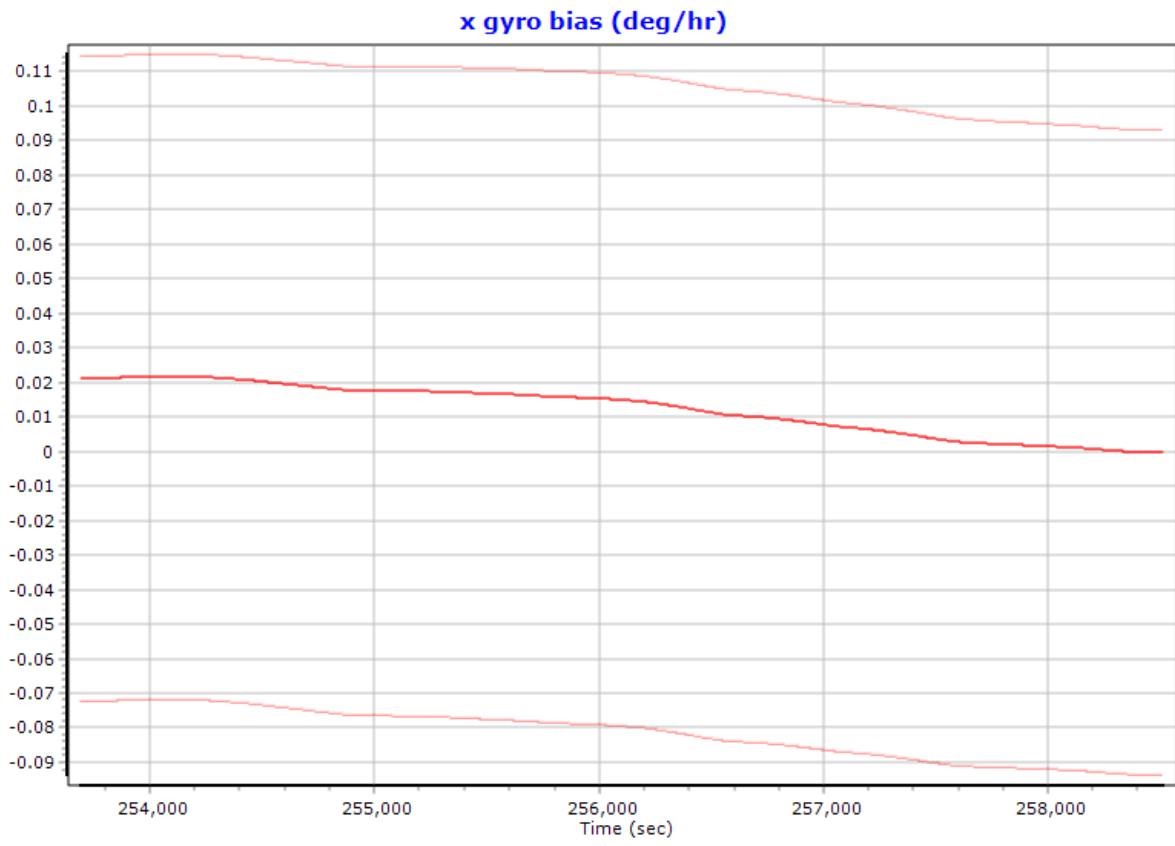
UTC Offset: 18.000

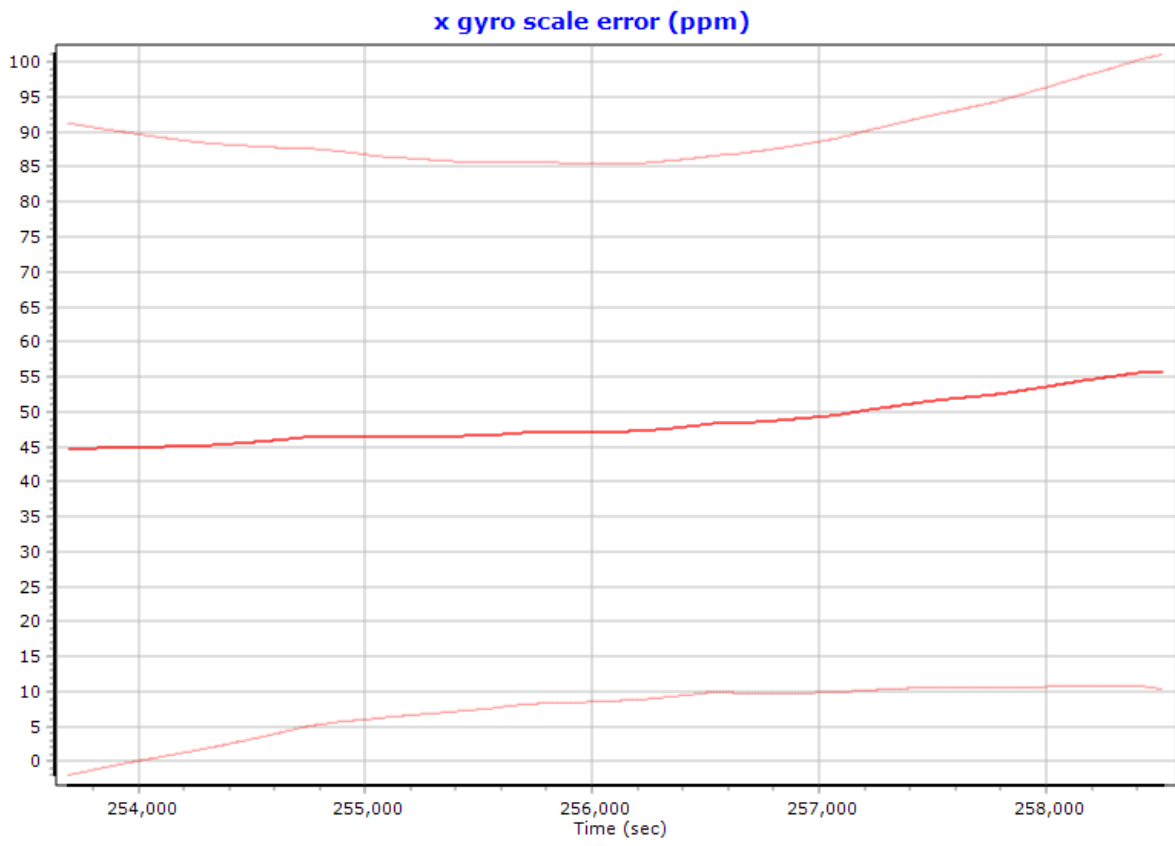
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

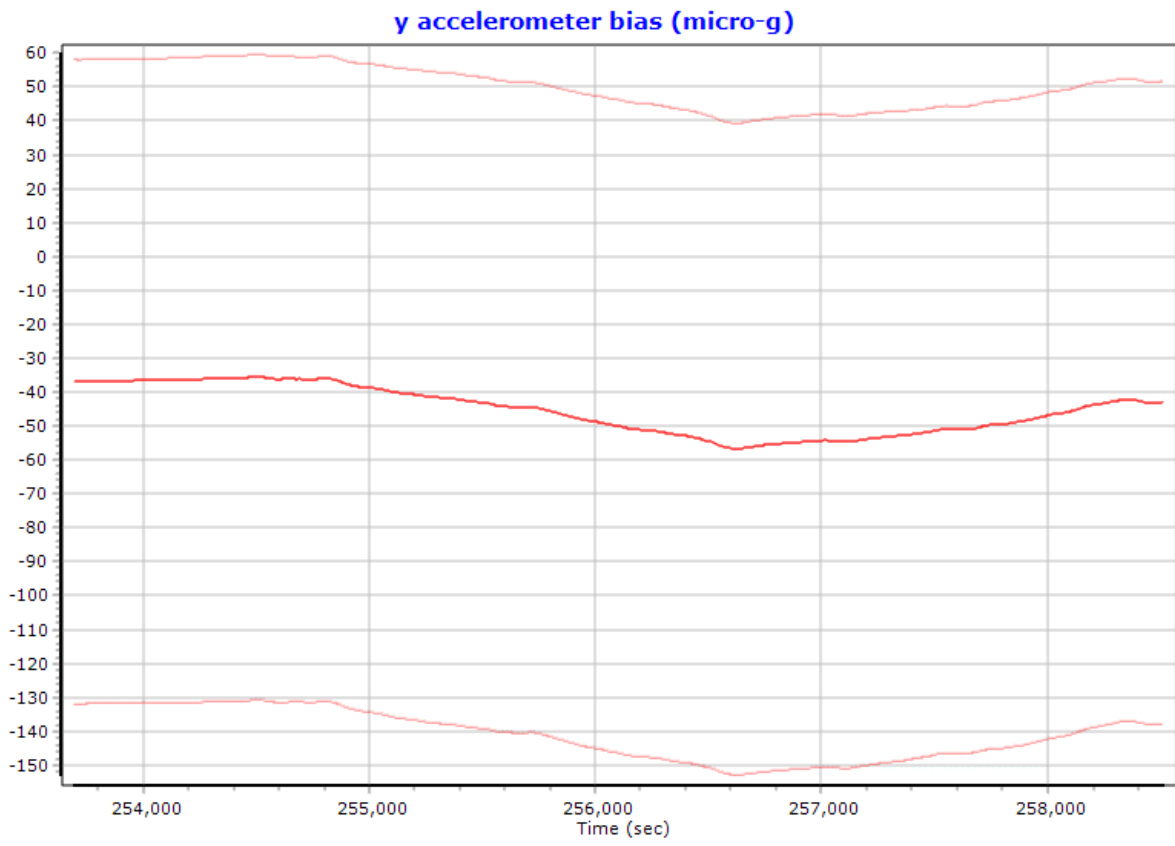
OK Cancel

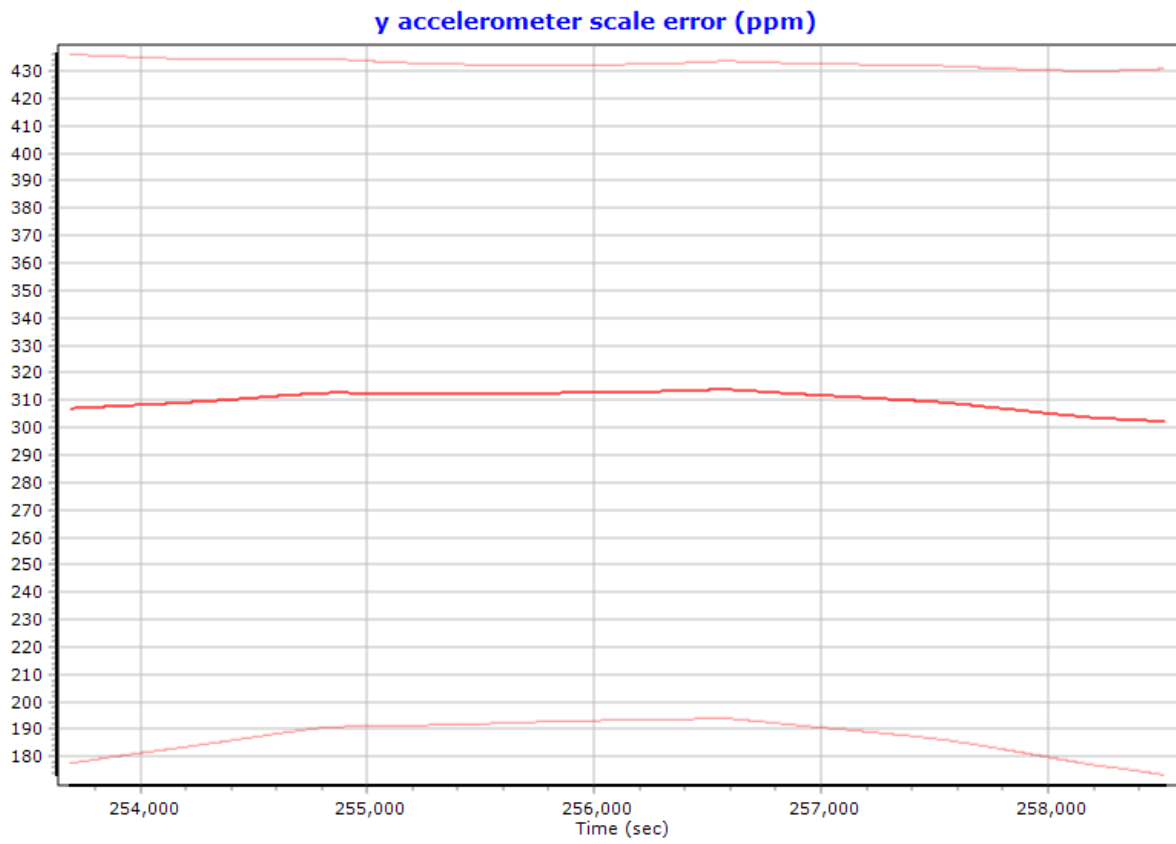


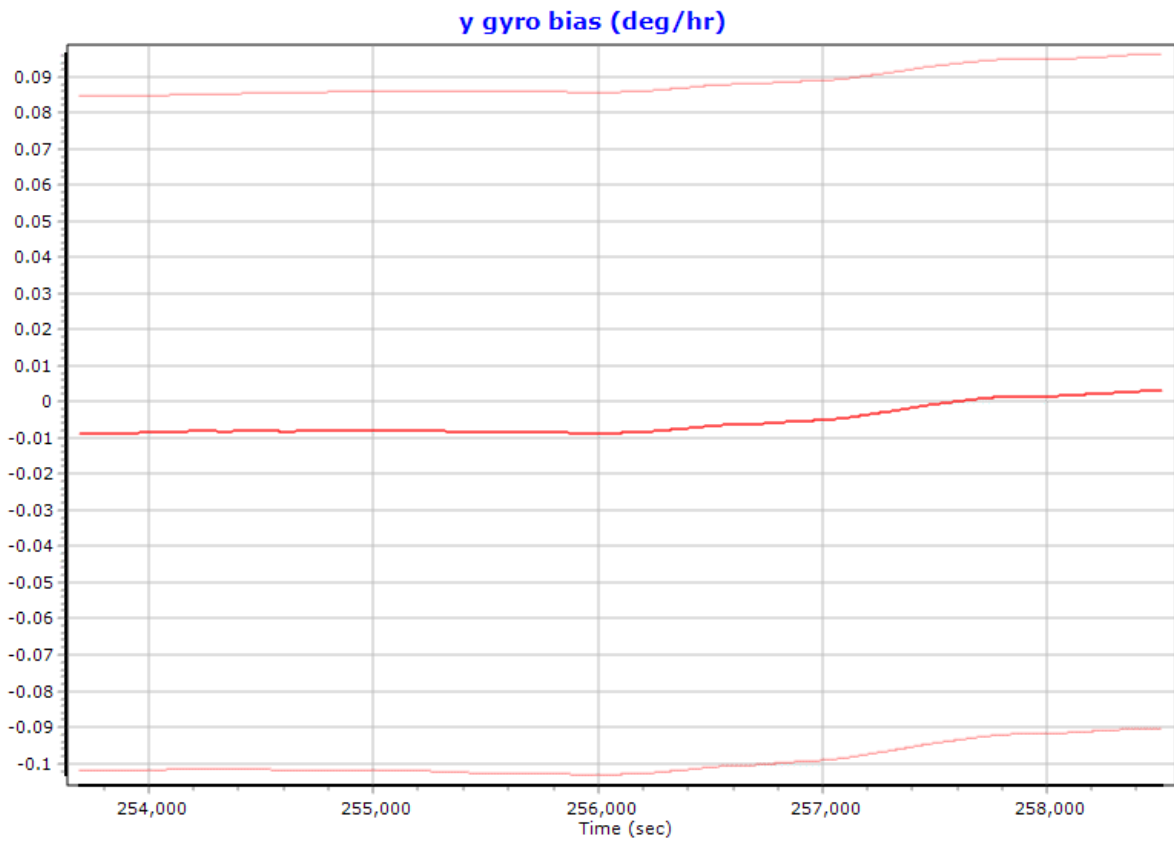


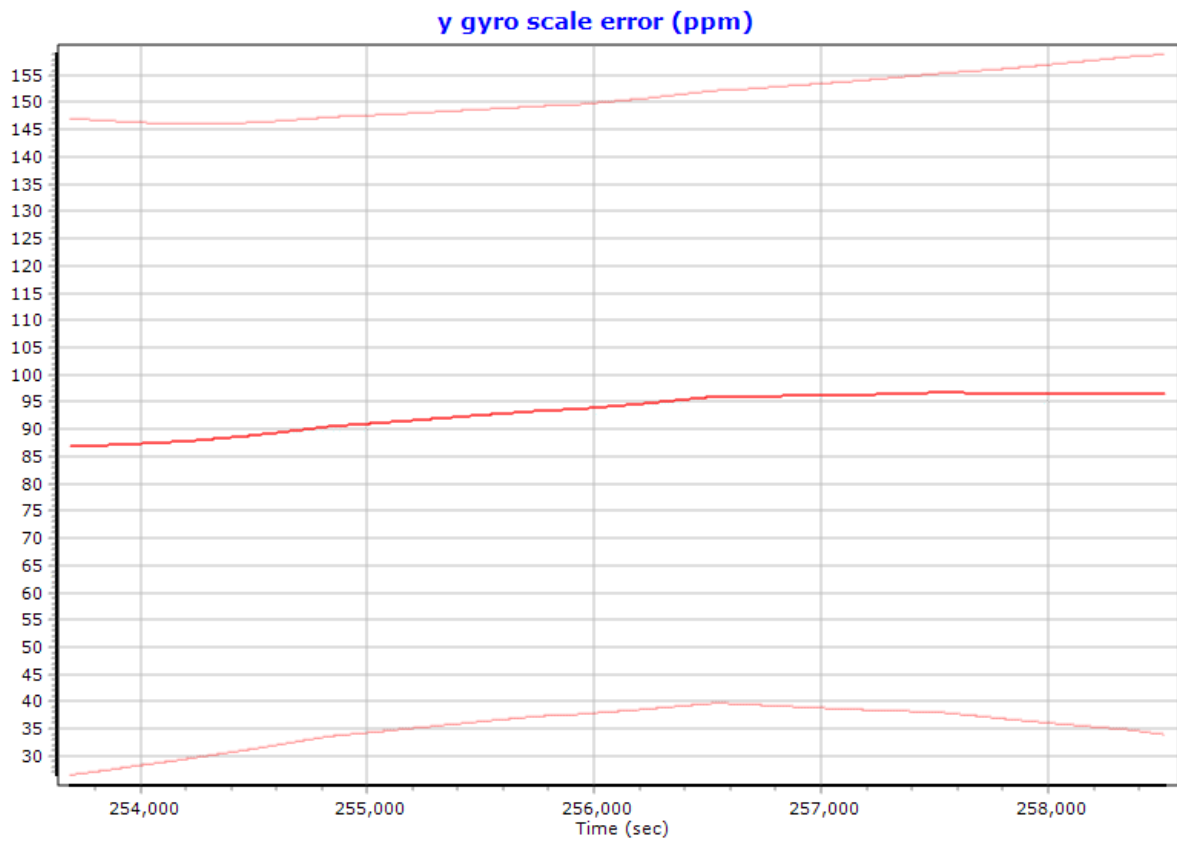


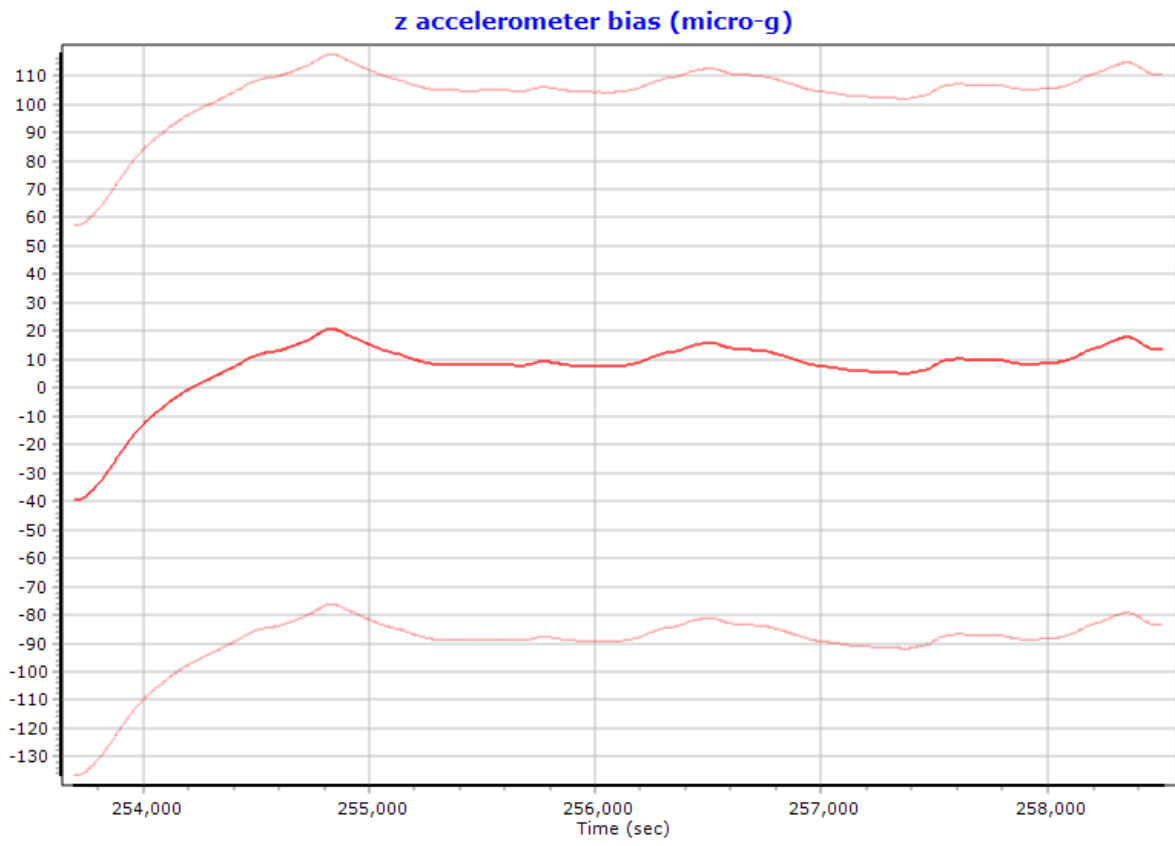


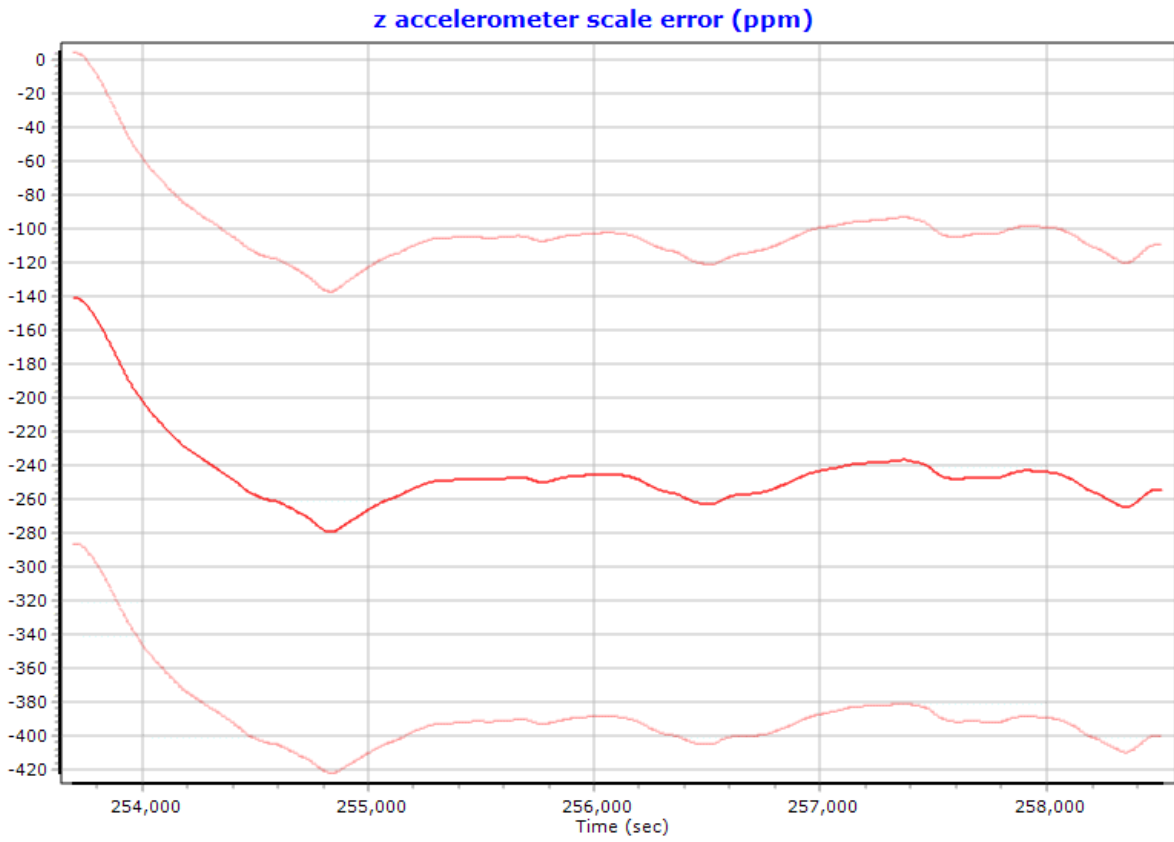


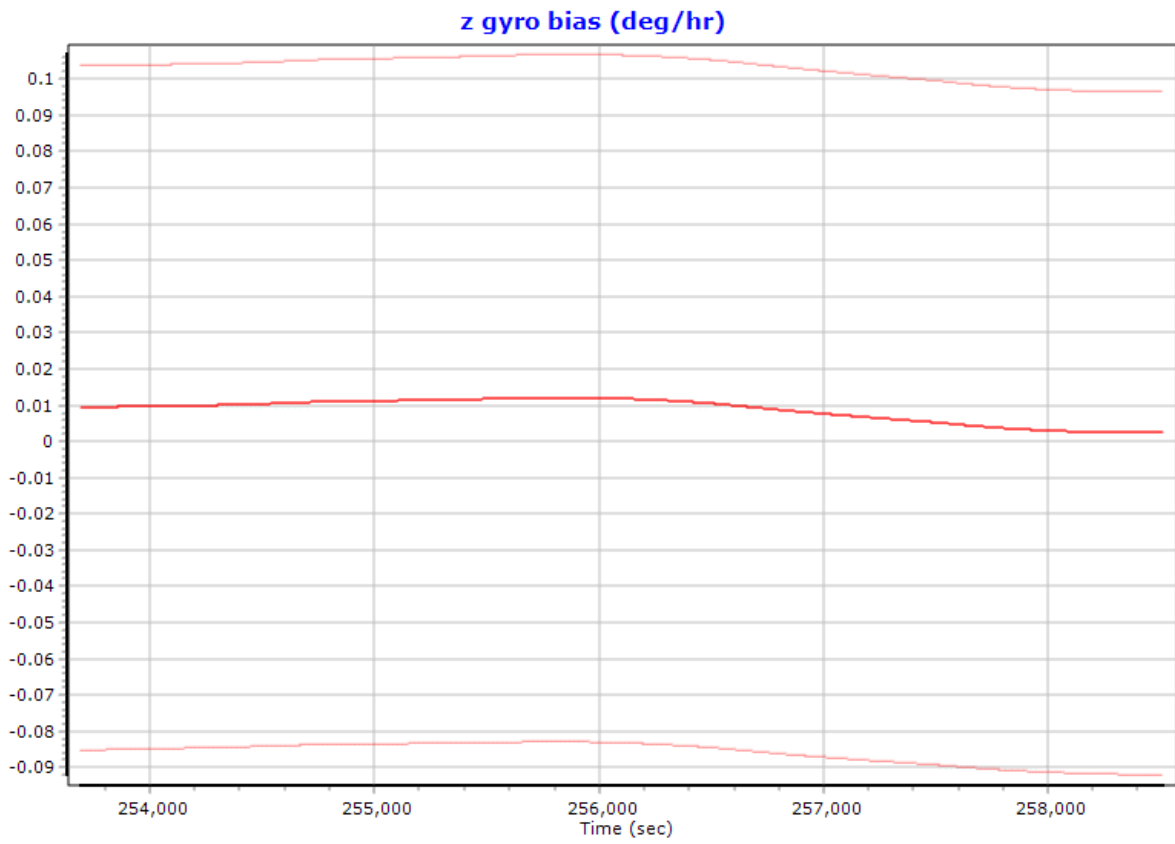


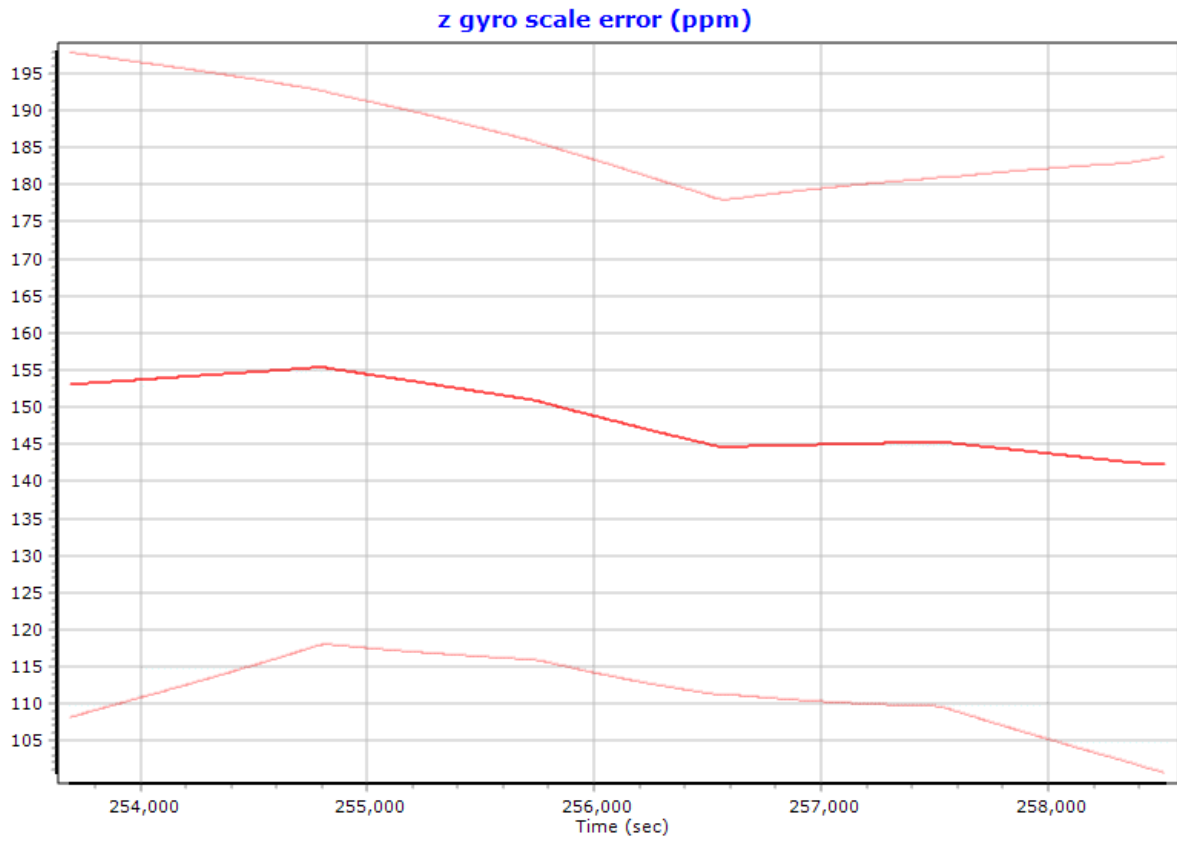




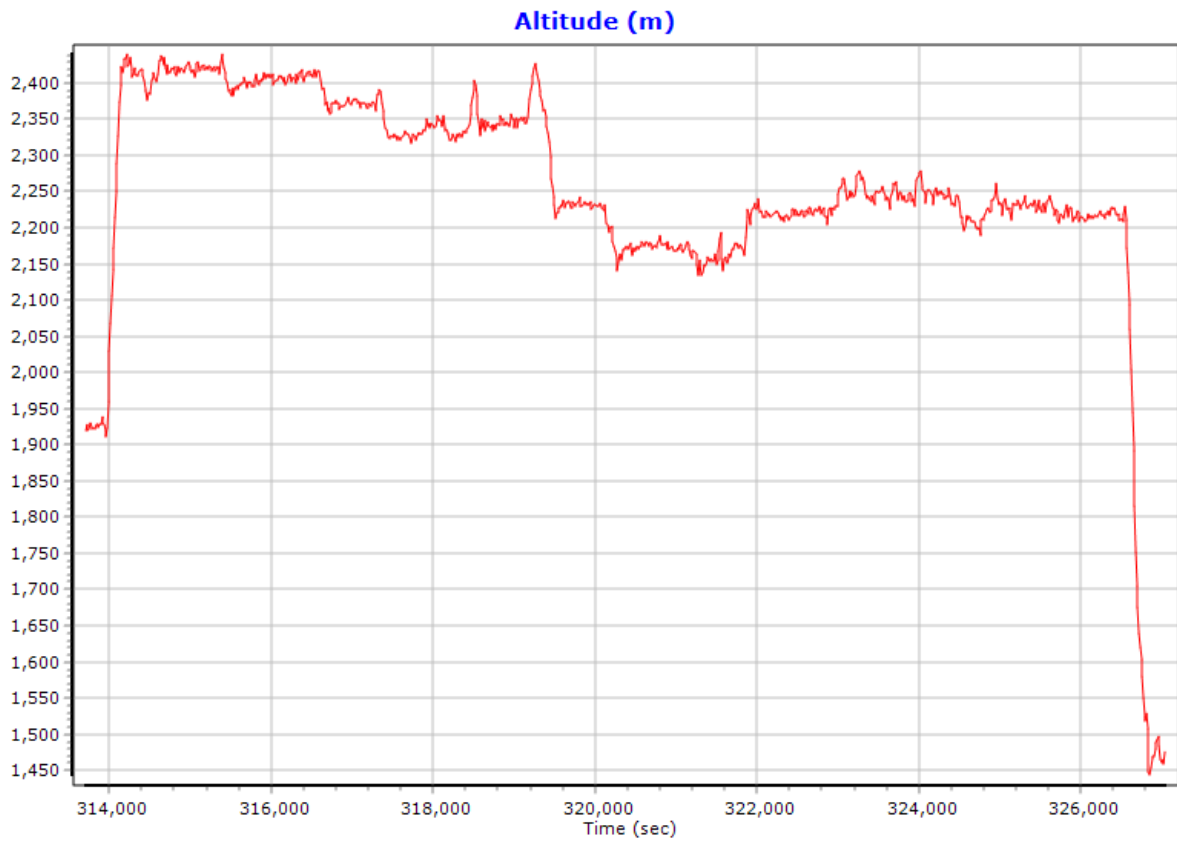


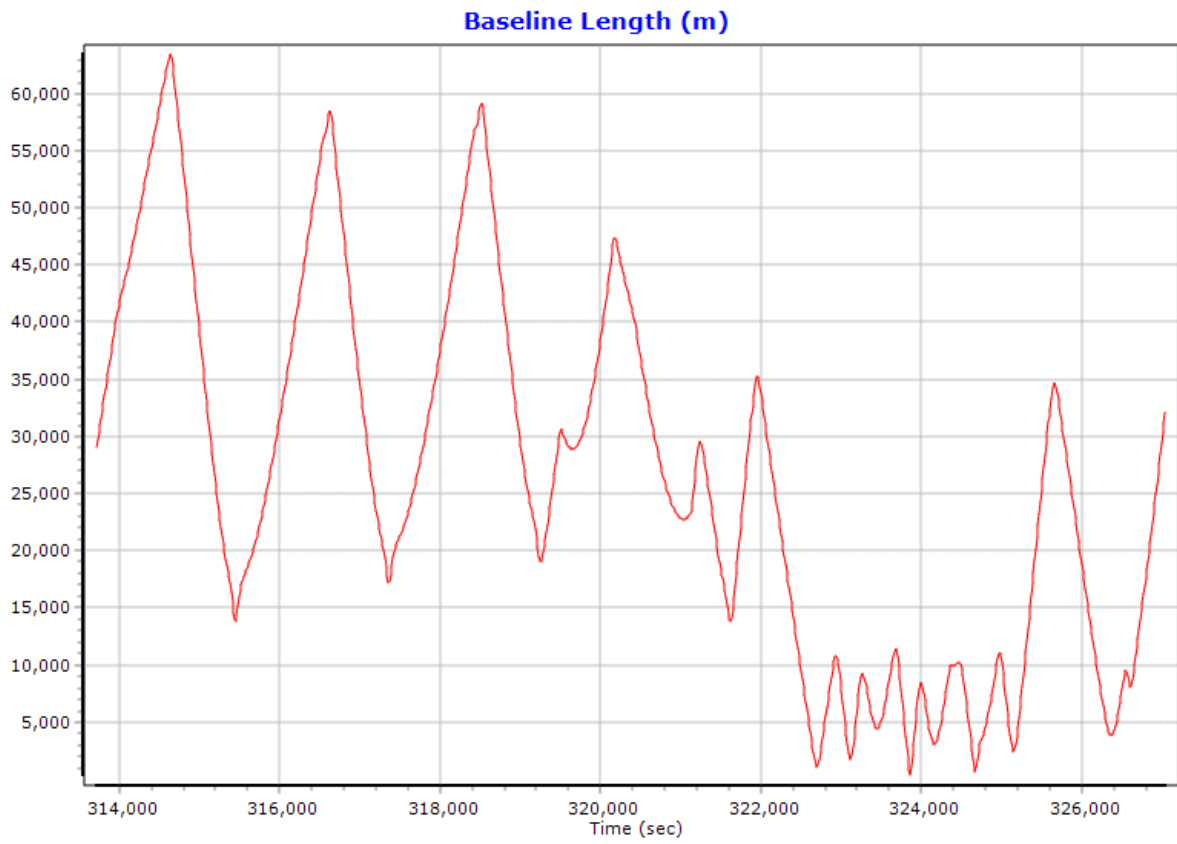


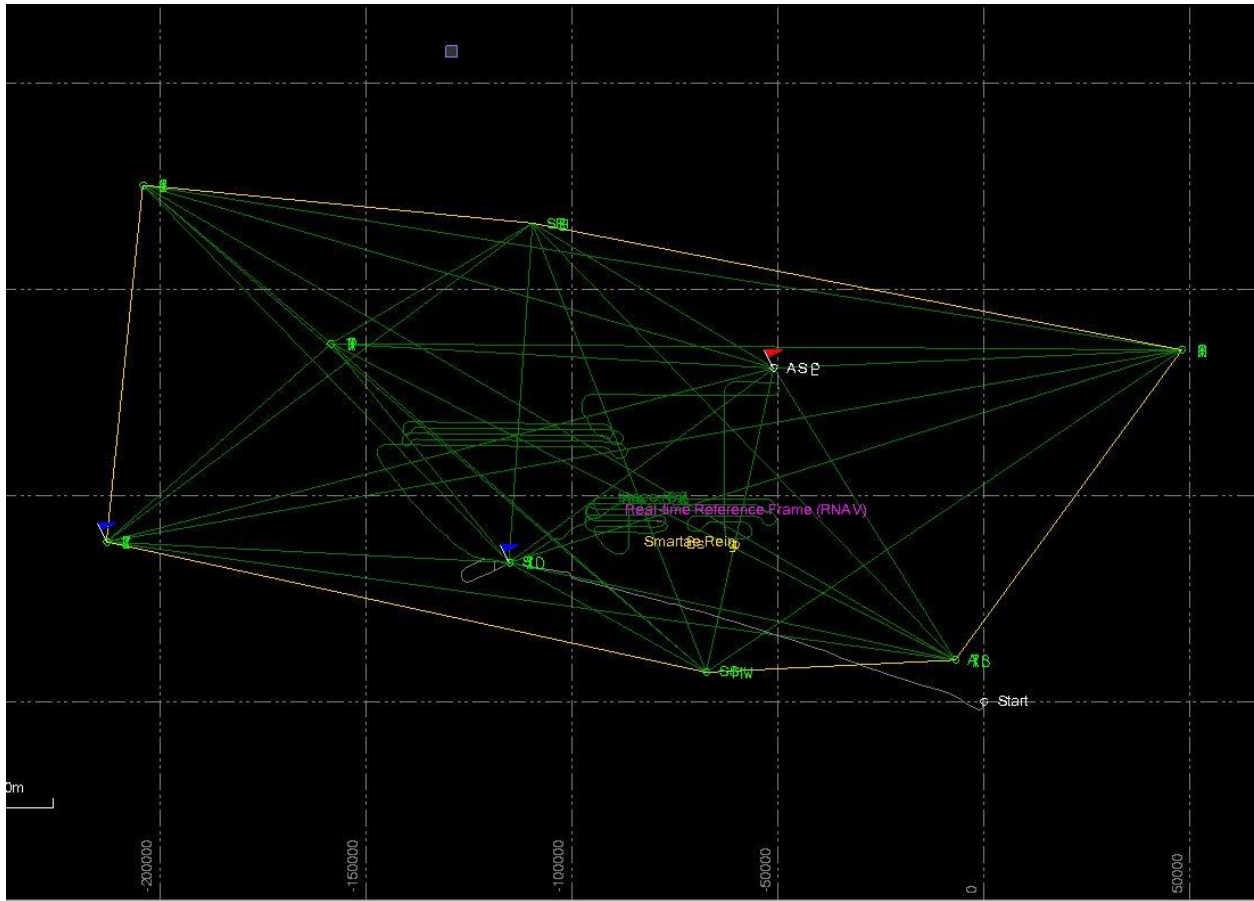


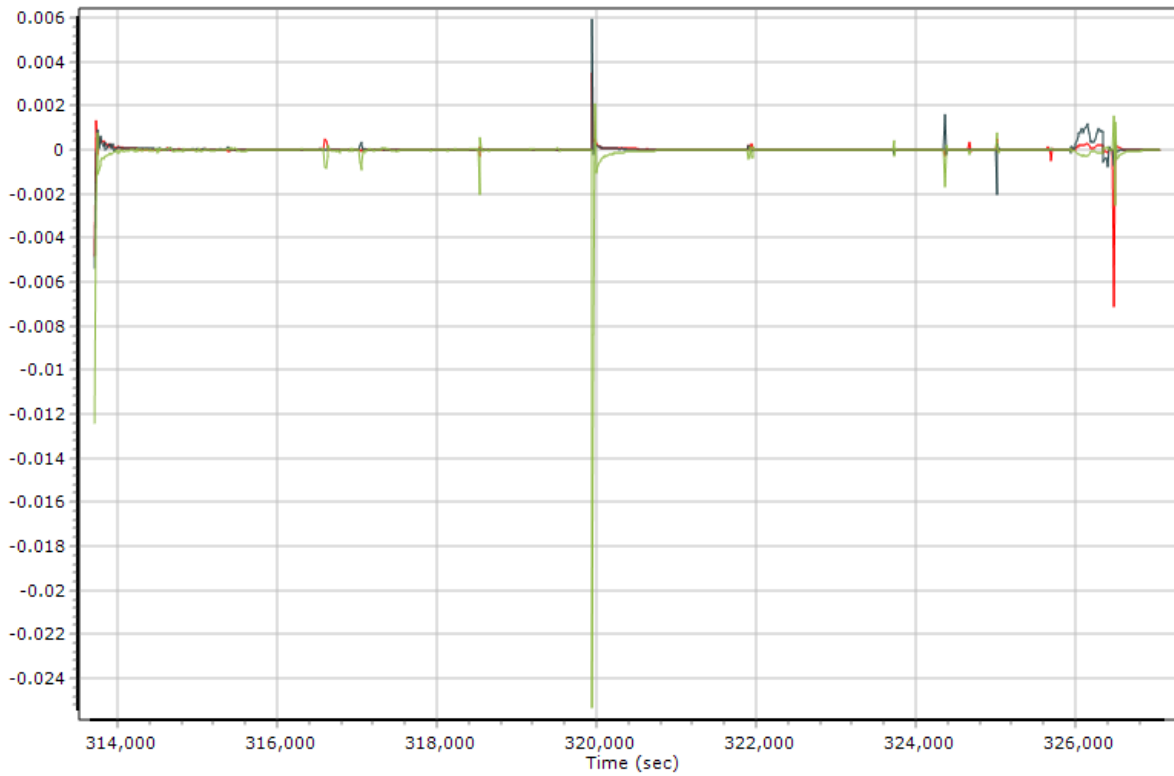


RBV18066A









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

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:

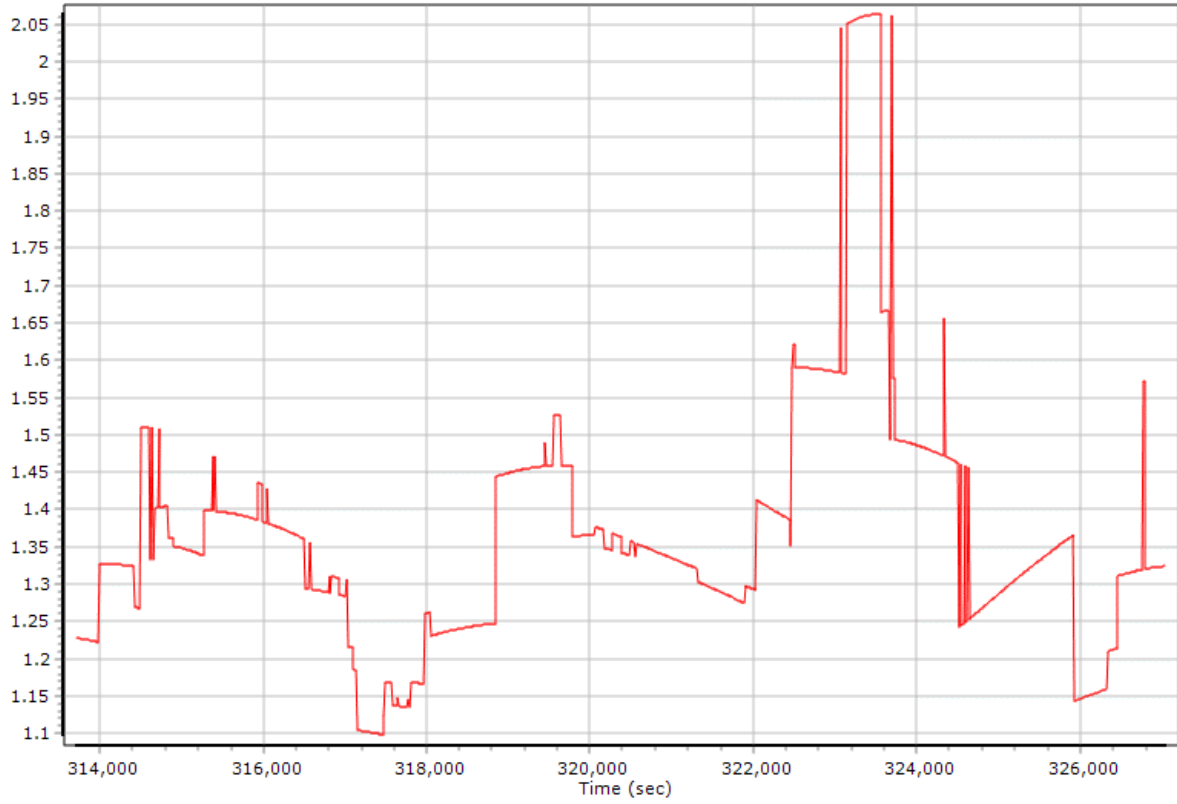
Standard Deviation

<3cm 10cm 50cm 1m 10m

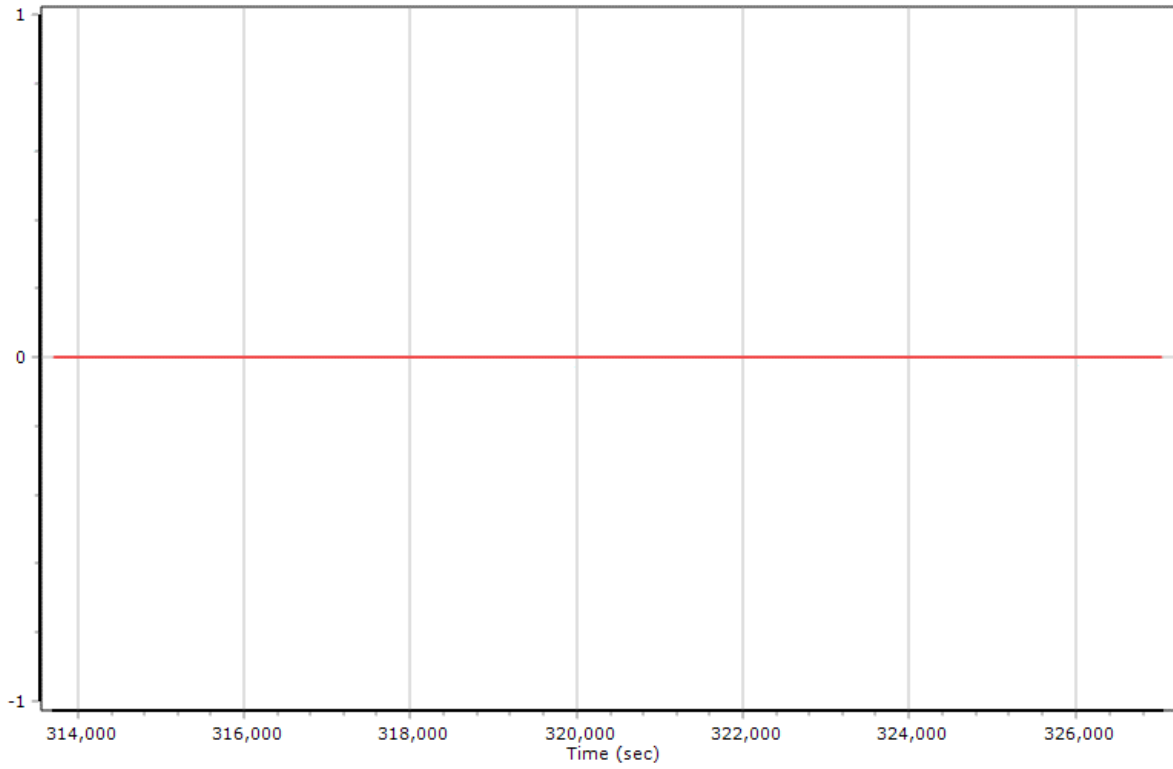
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

OK Cancel

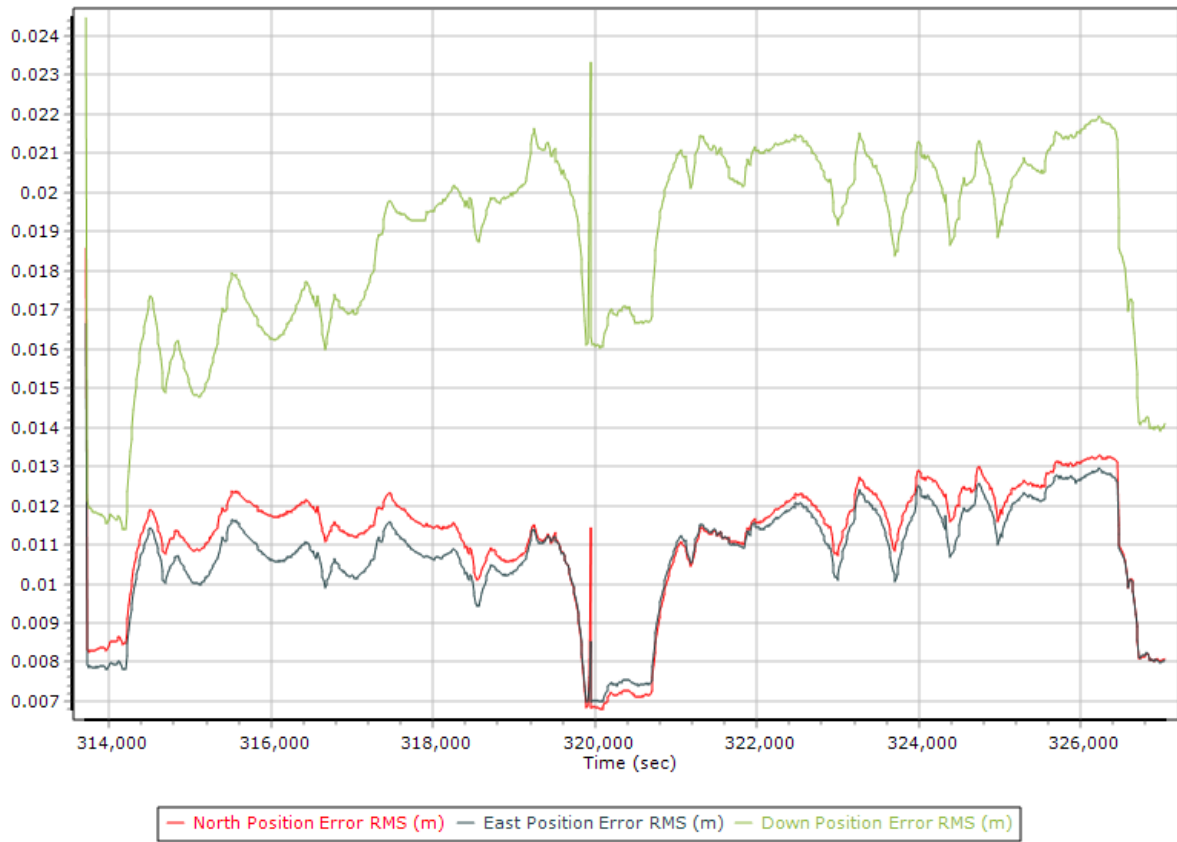
PDOP

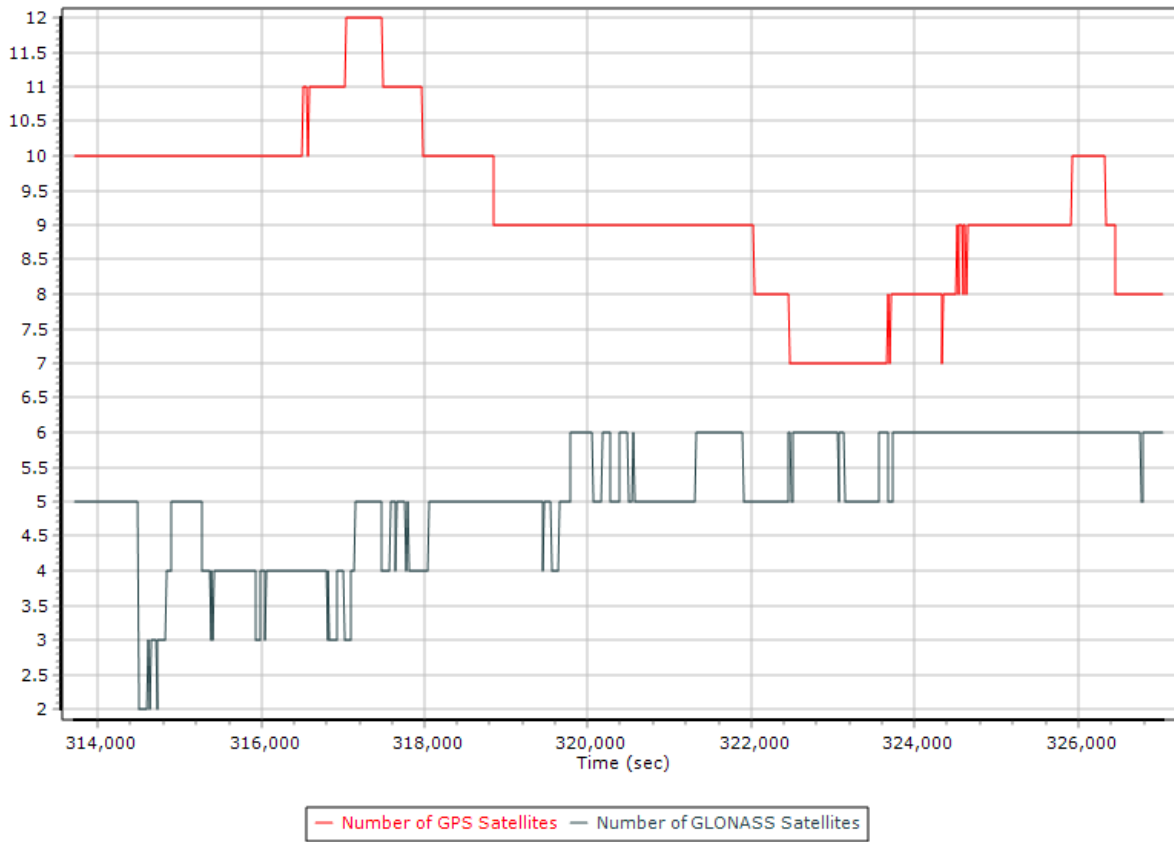


Processing mode



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





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: 313710.434

End: 327064.507

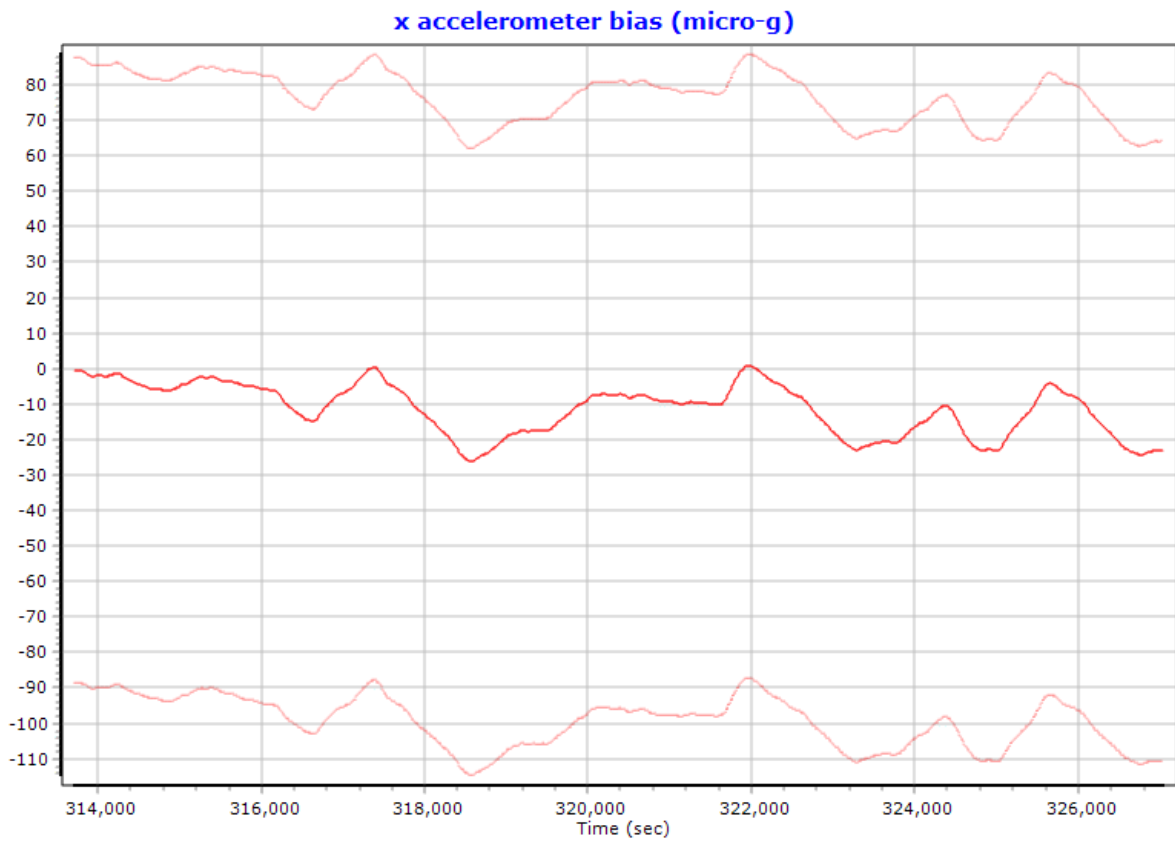
Entire time interval

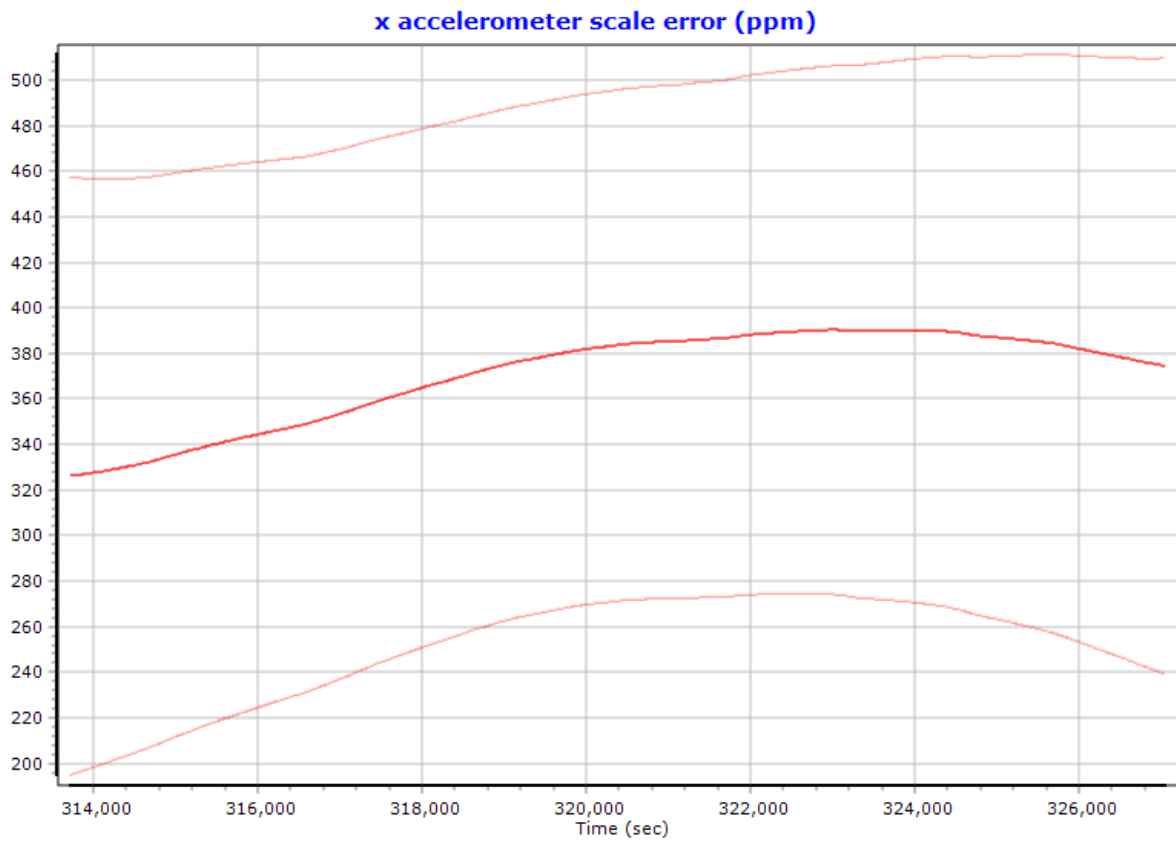
Seconds of start week

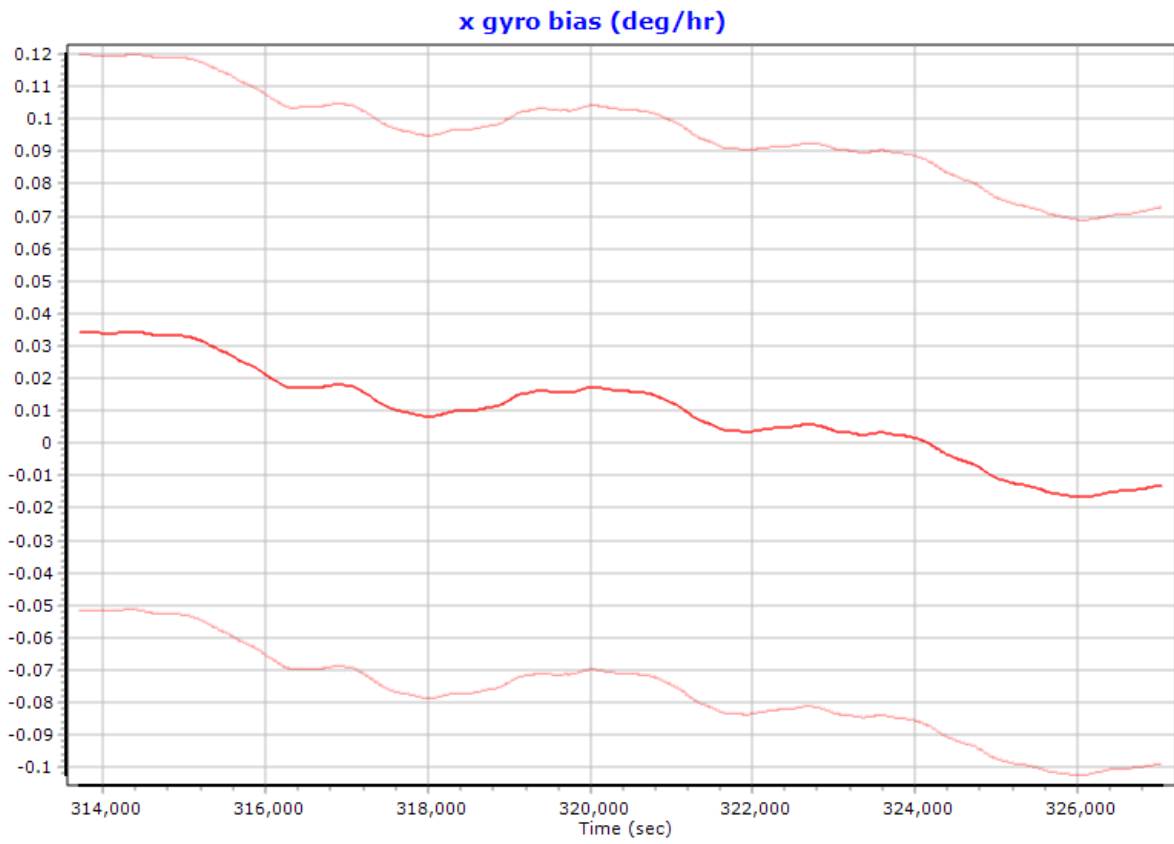
UTC Offset: 18.000

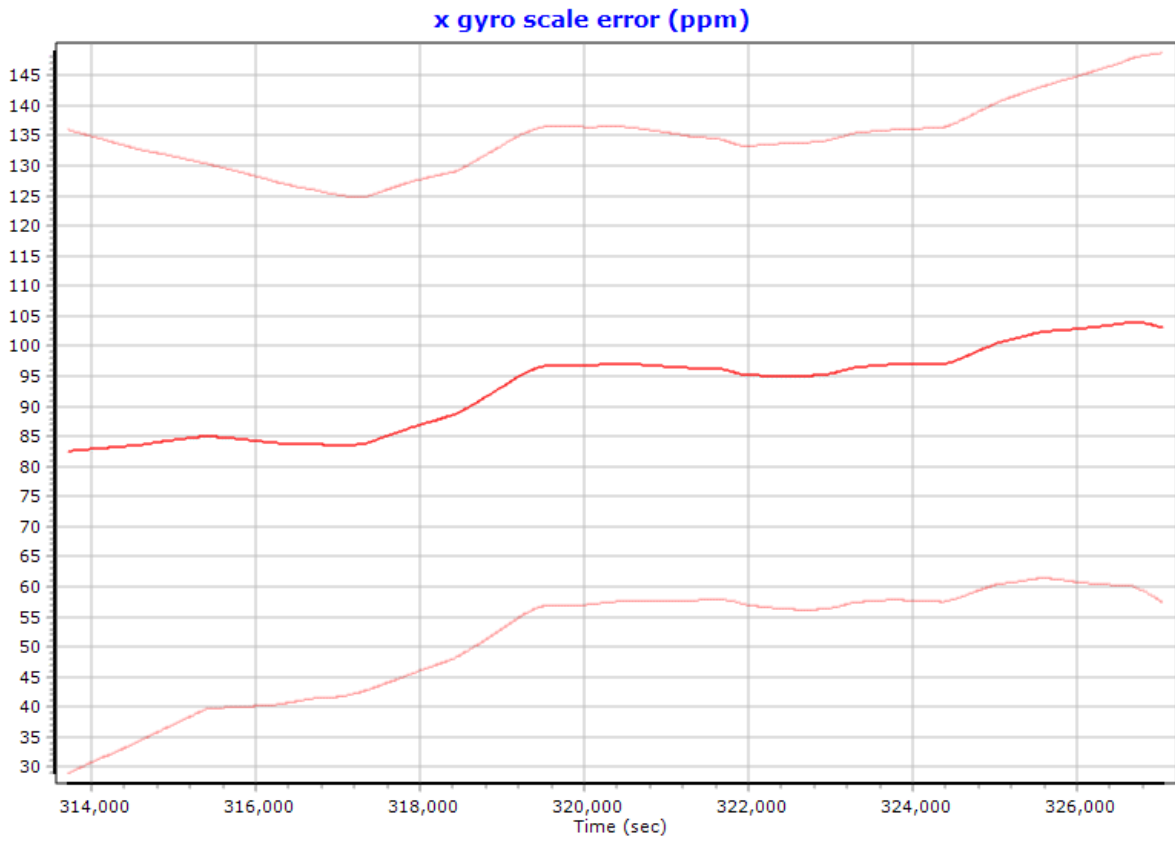
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

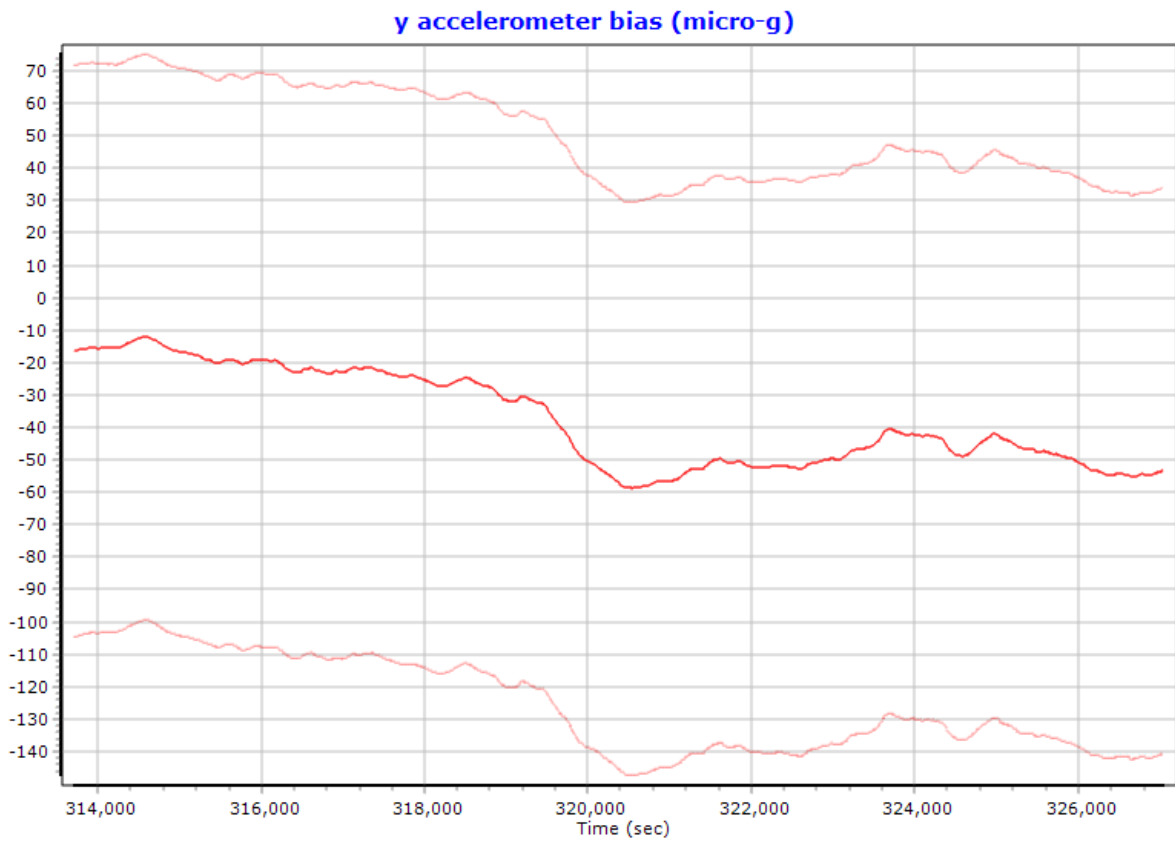
OK Cancel

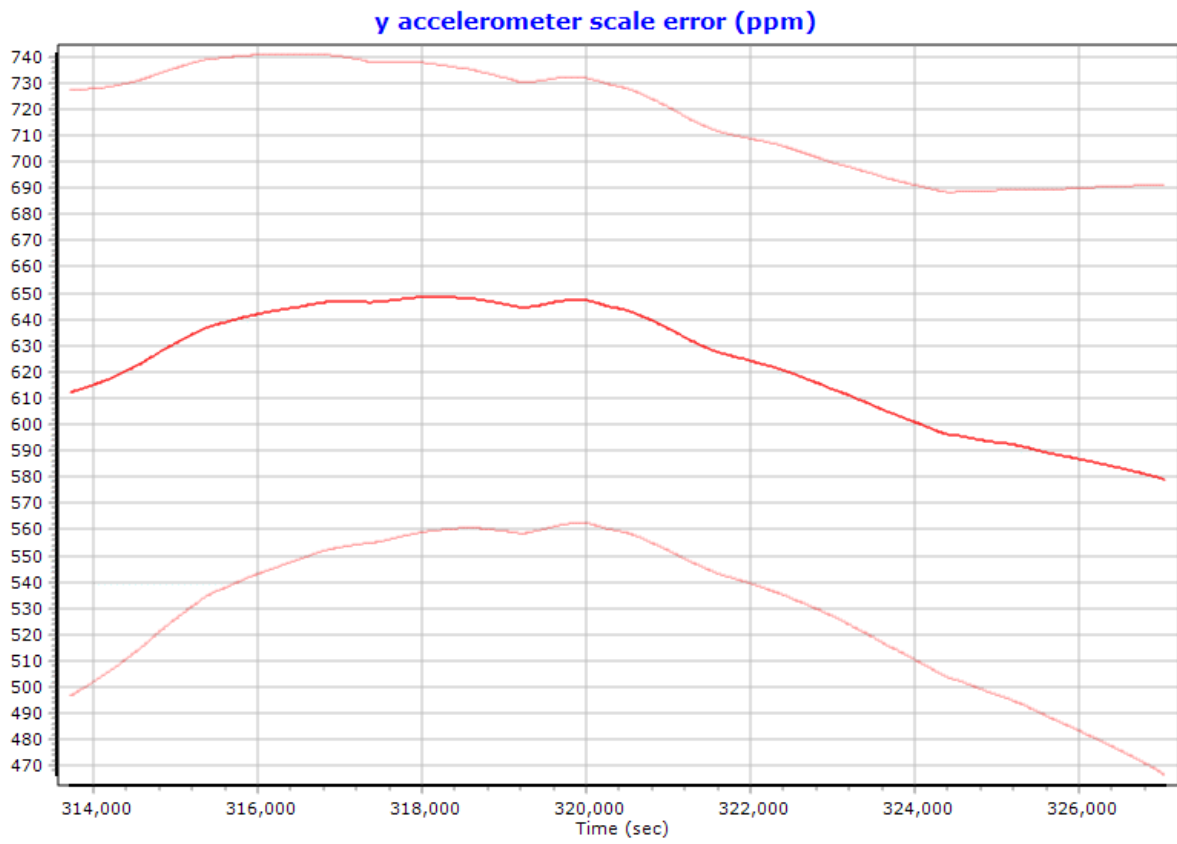


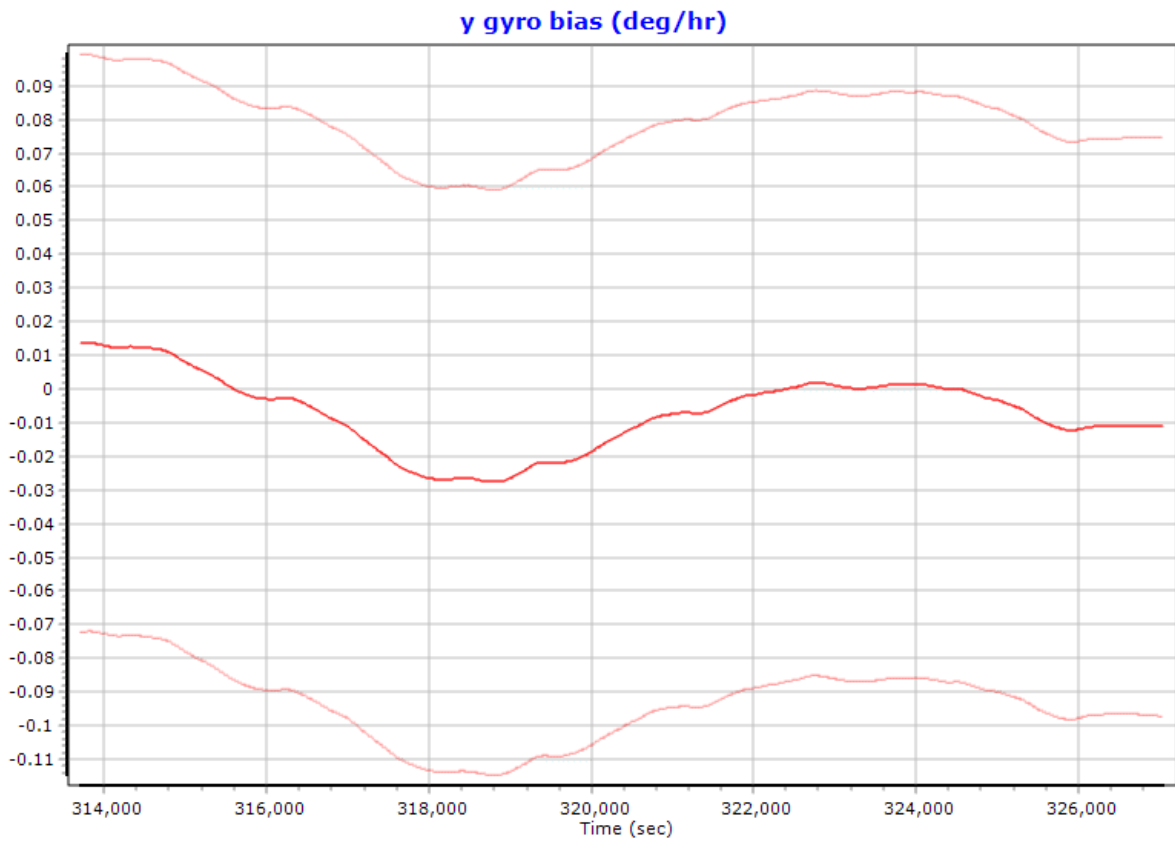


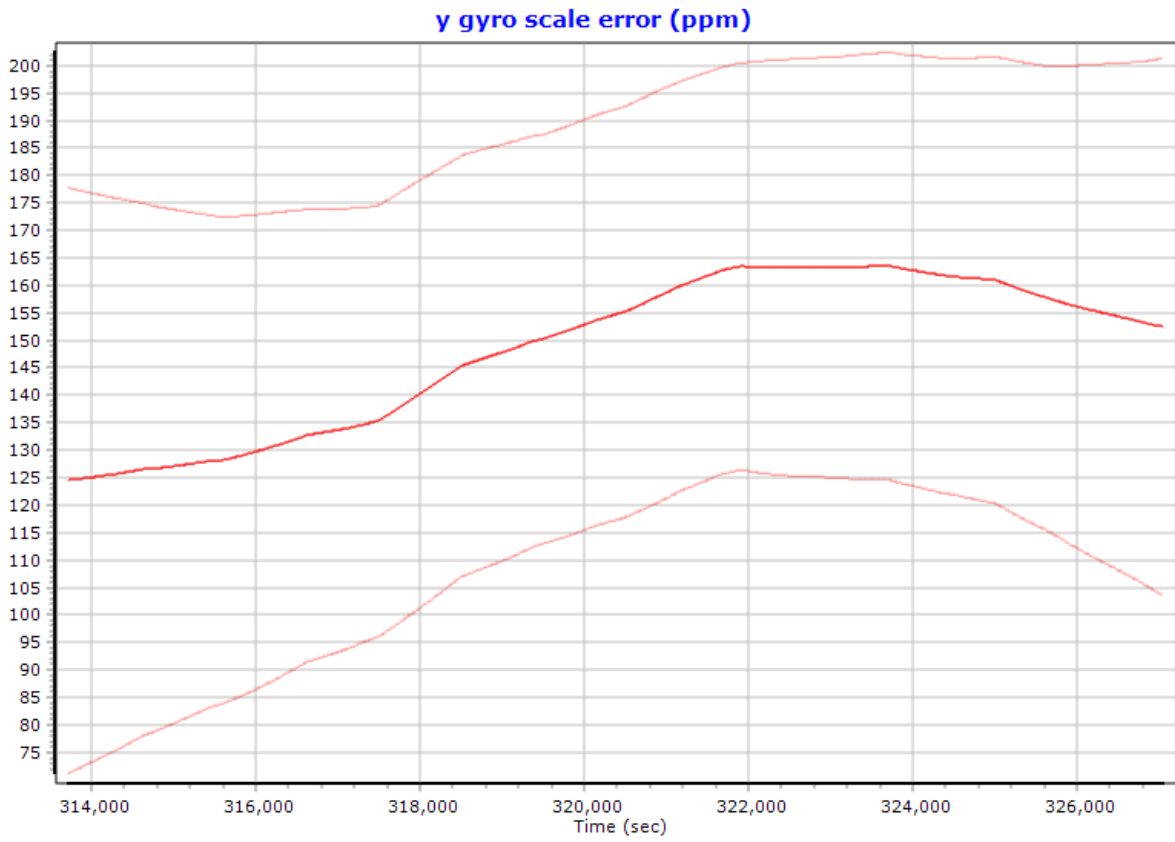


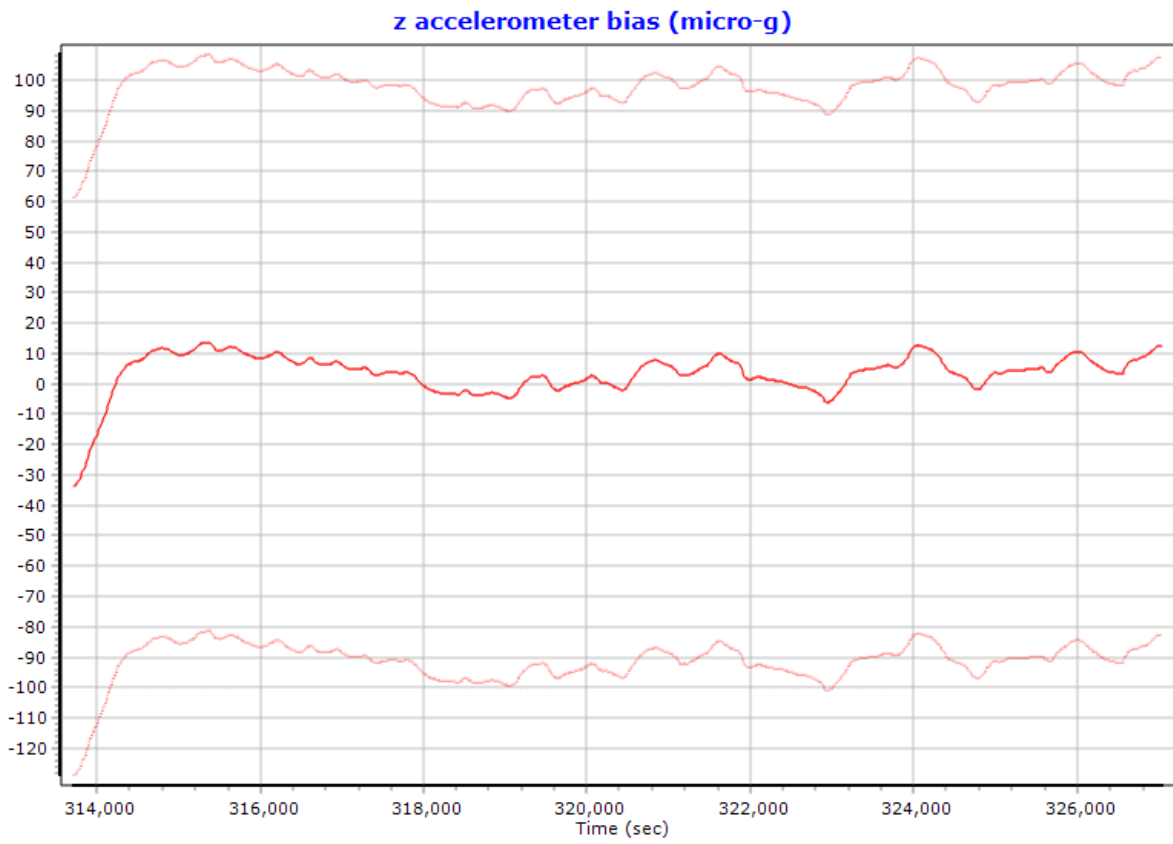


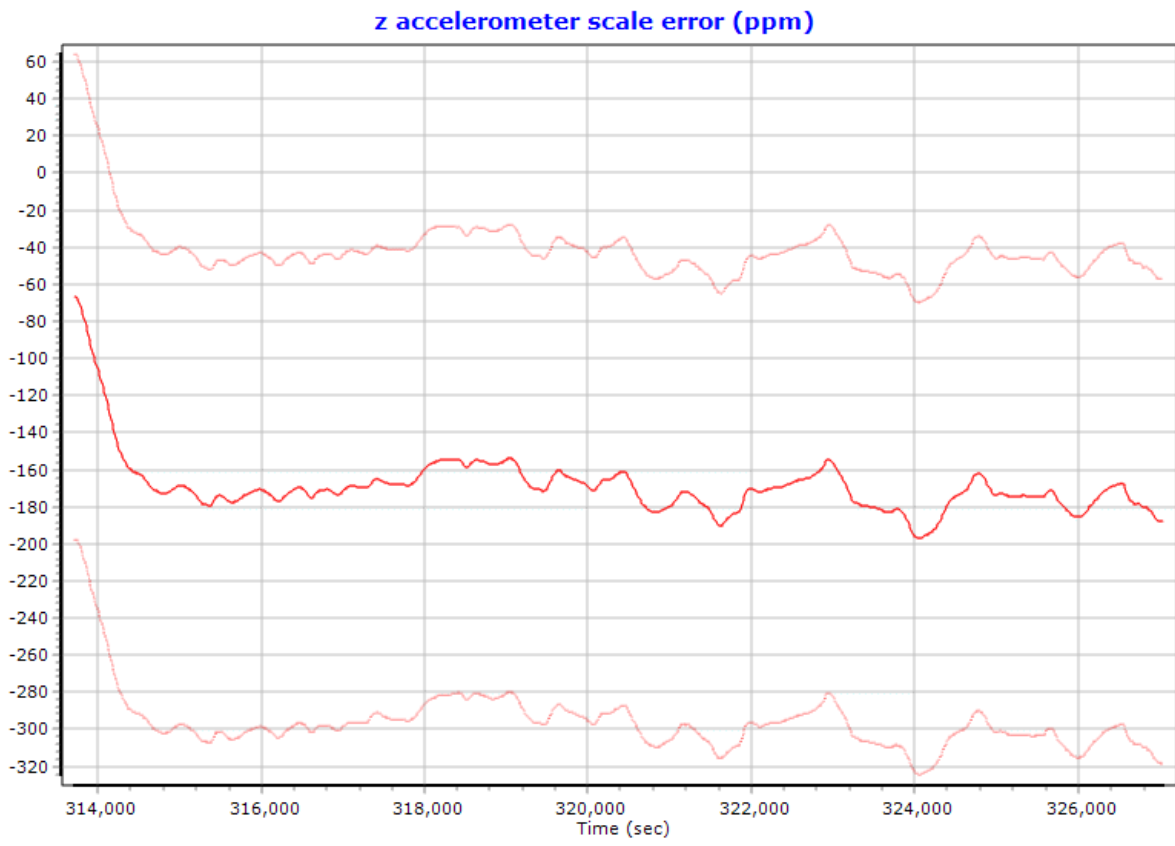


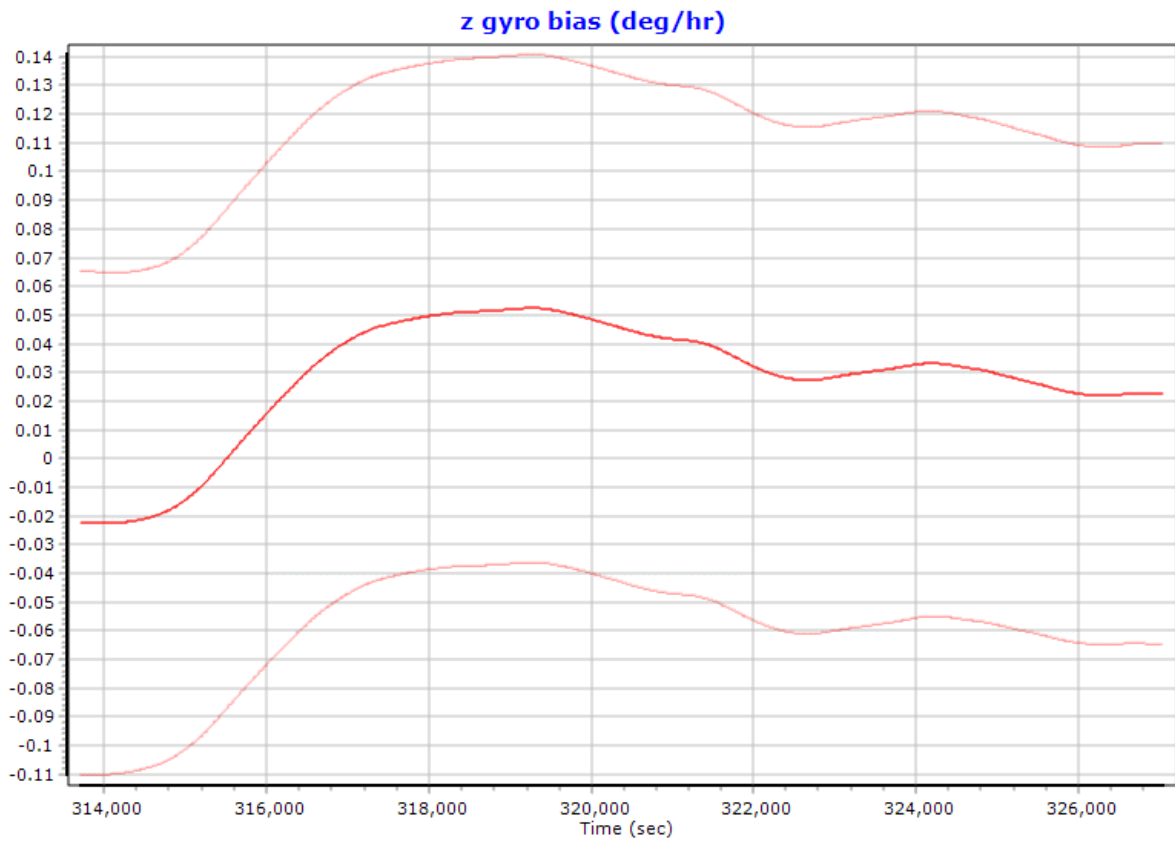


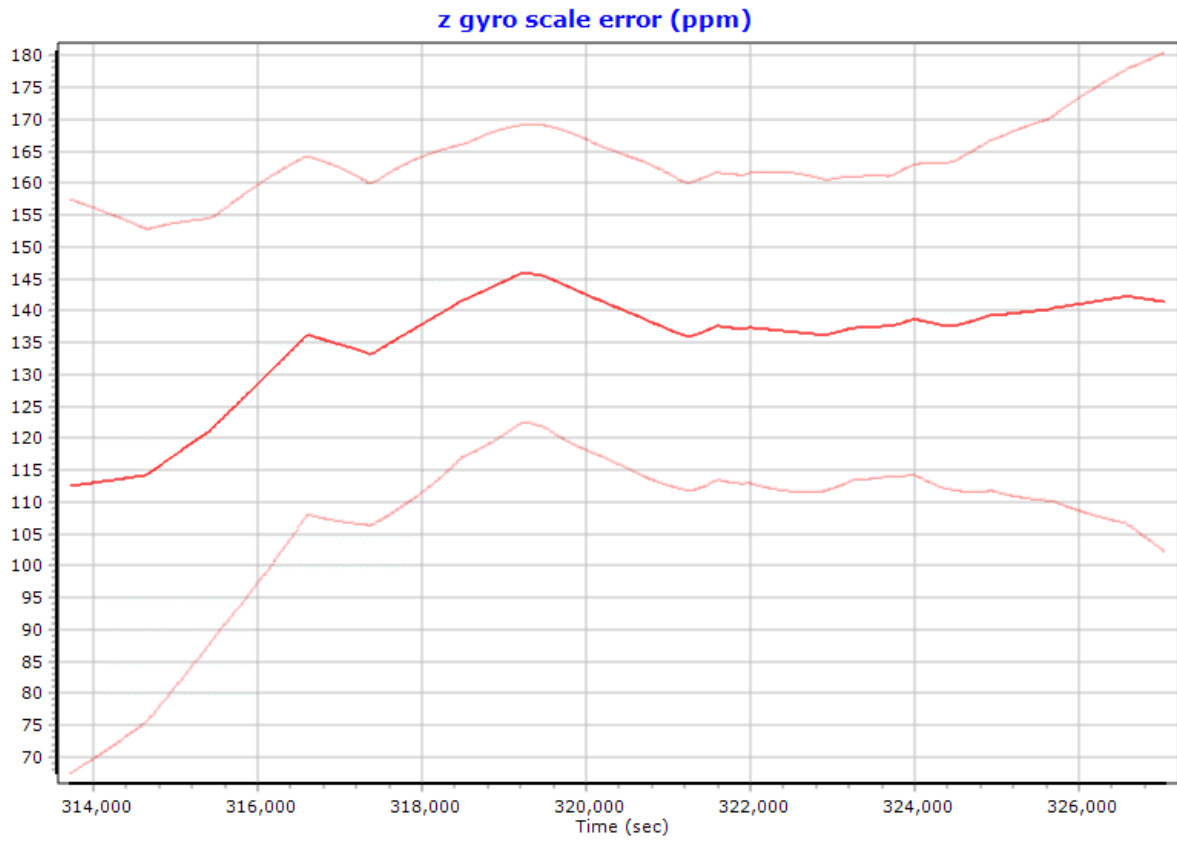




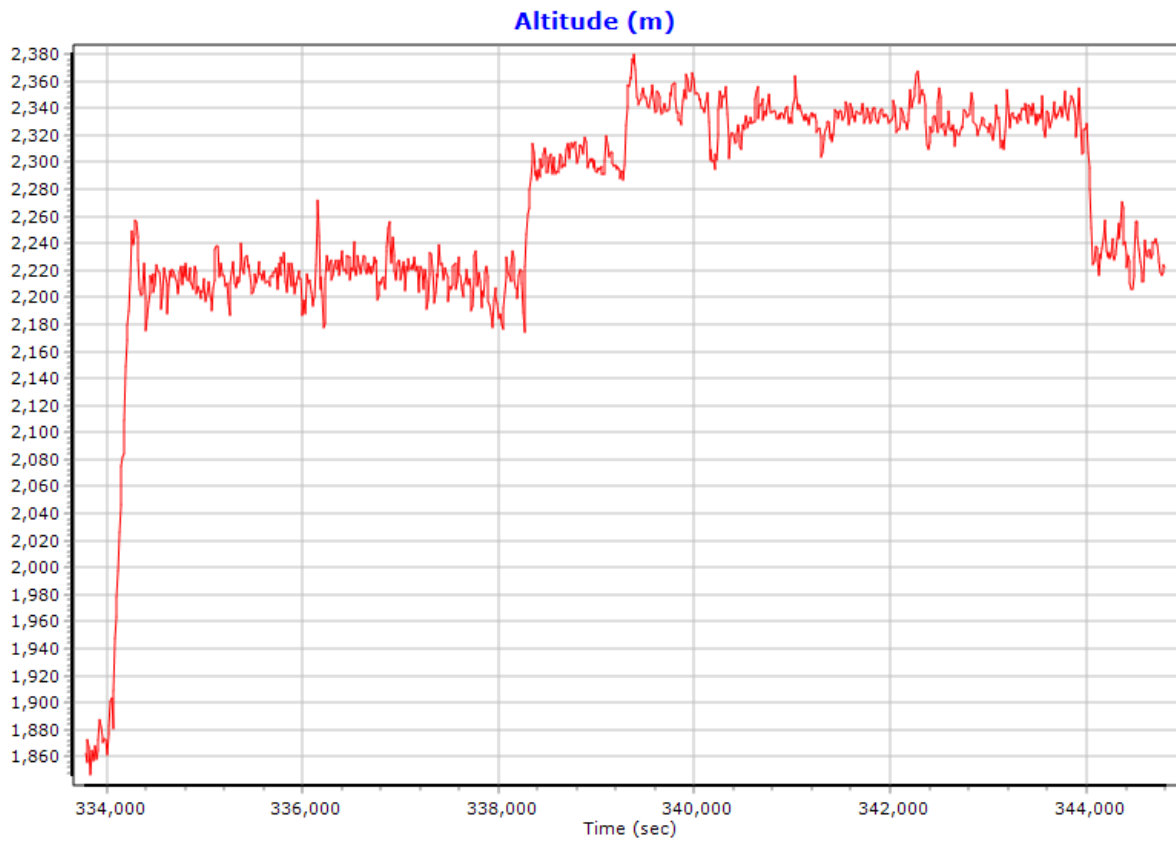


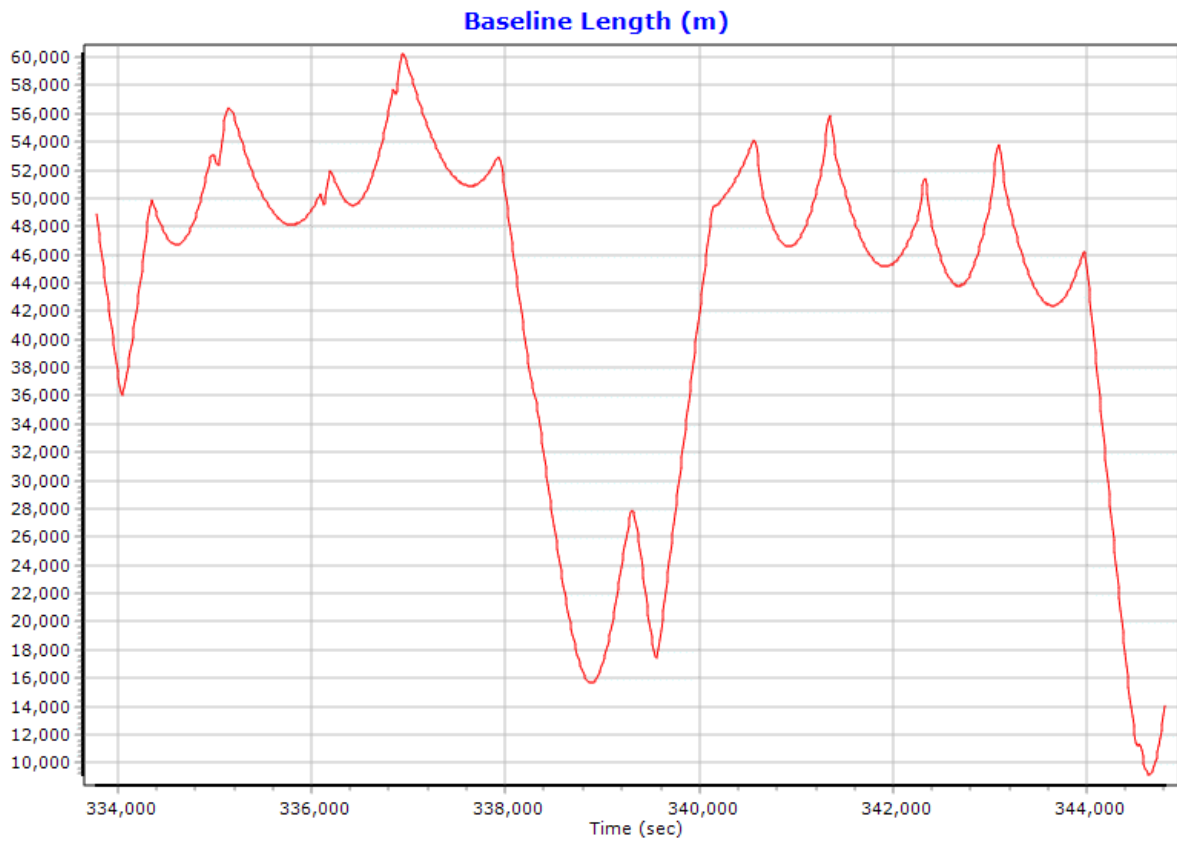


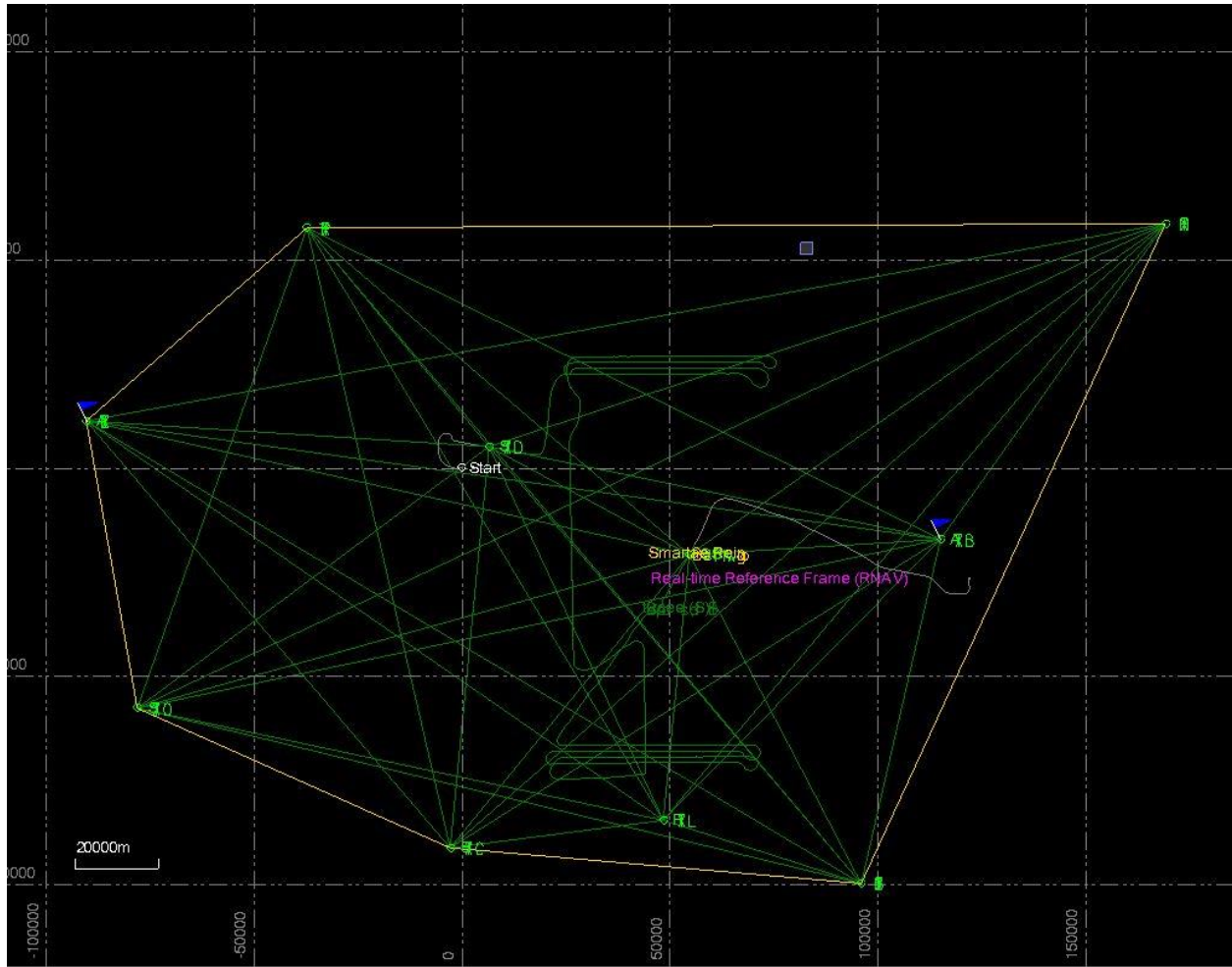


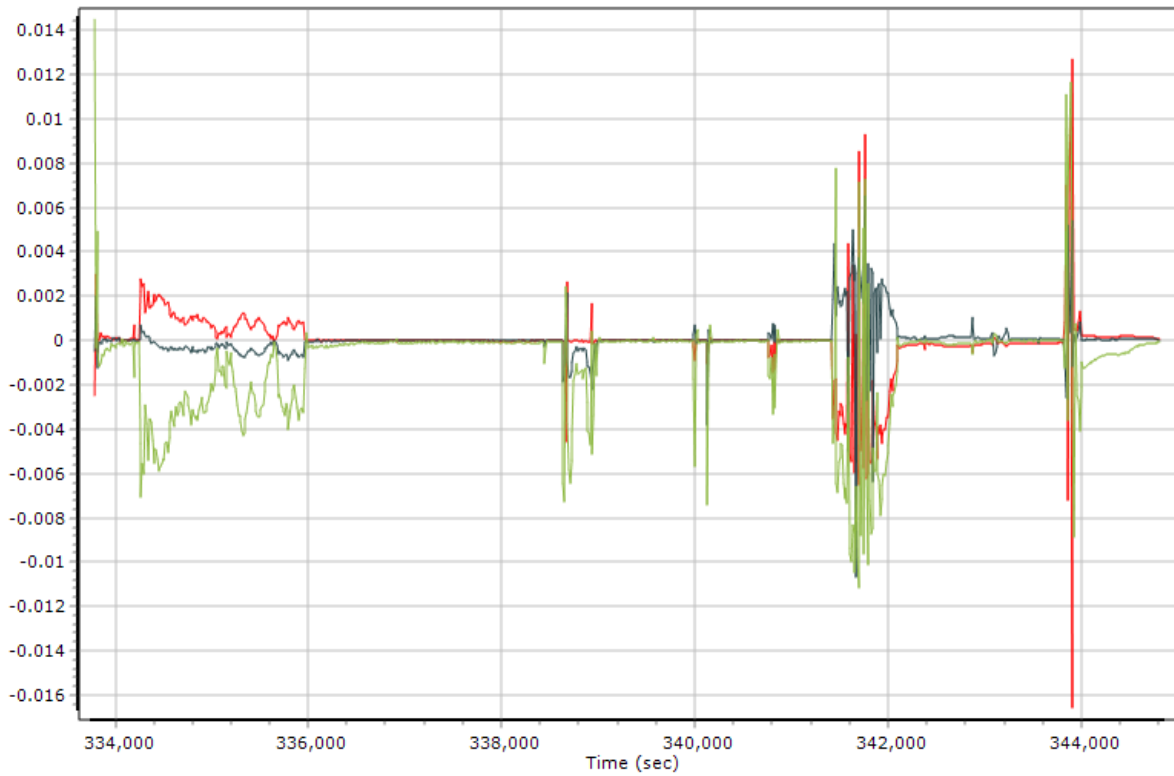


RBV18066B









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

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

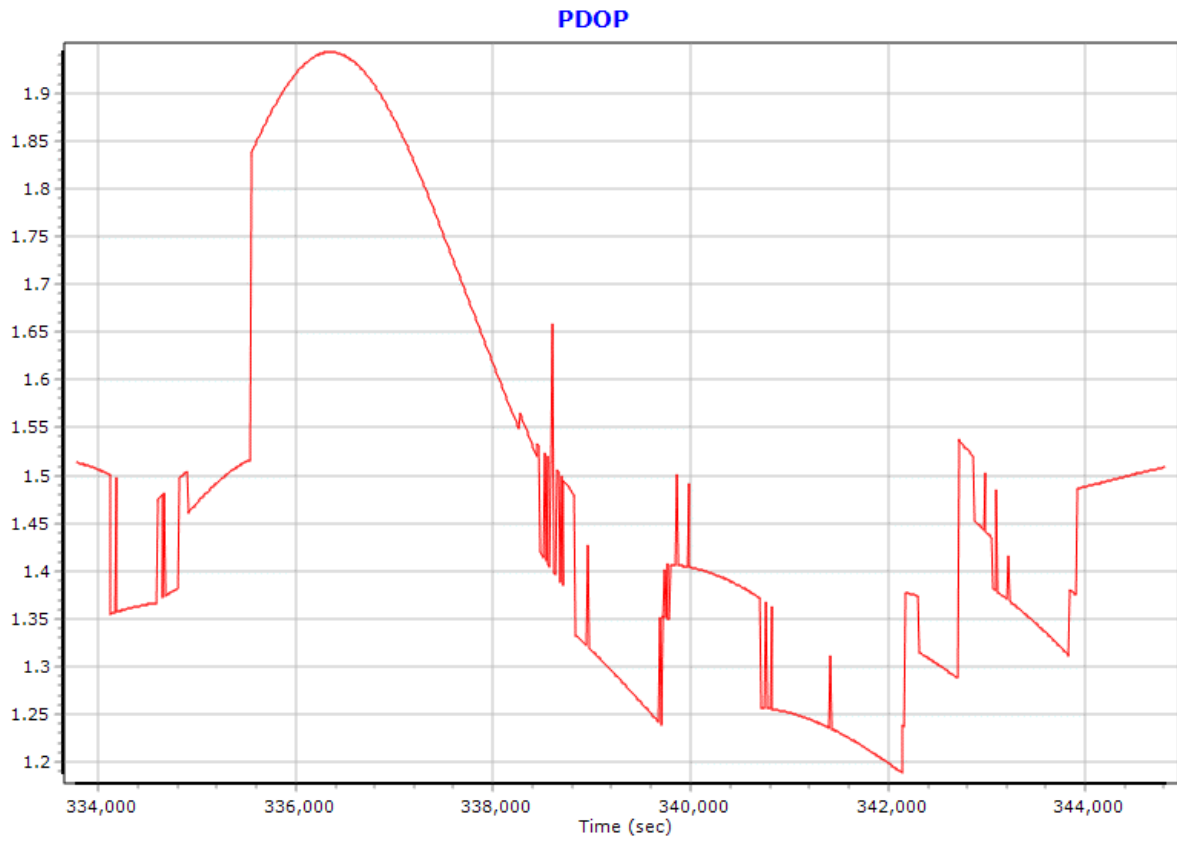
X

Y

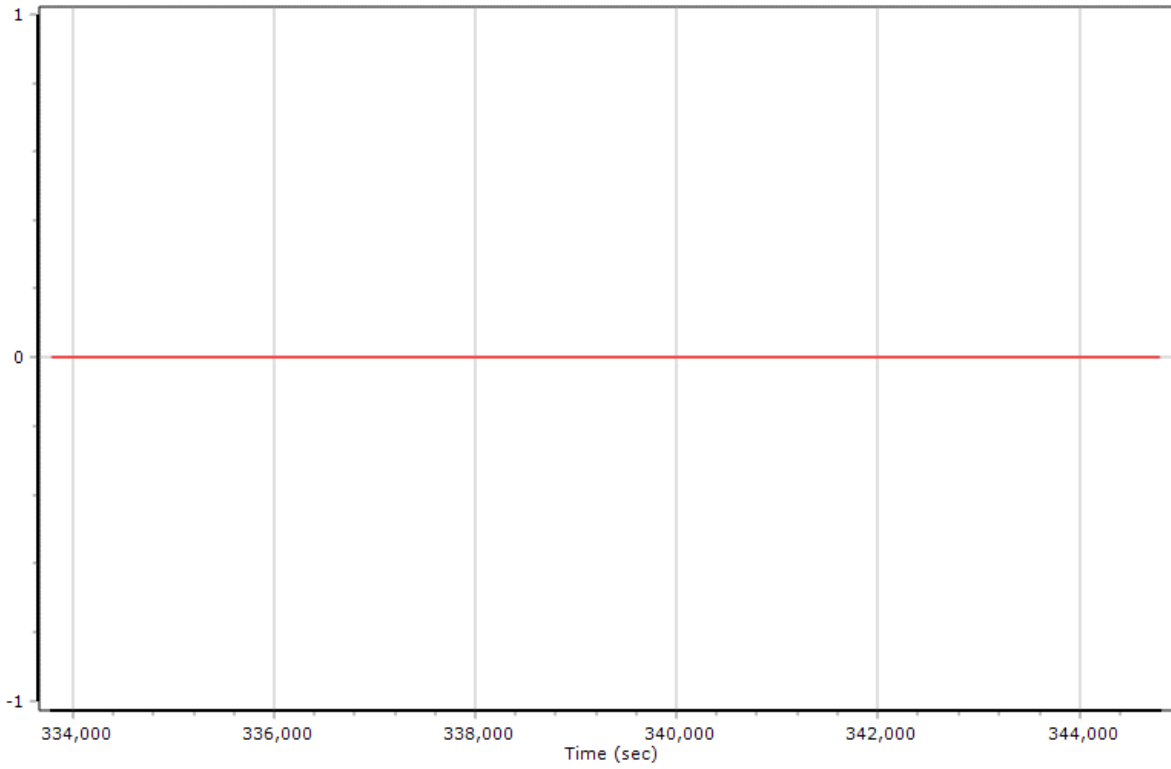
Z

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

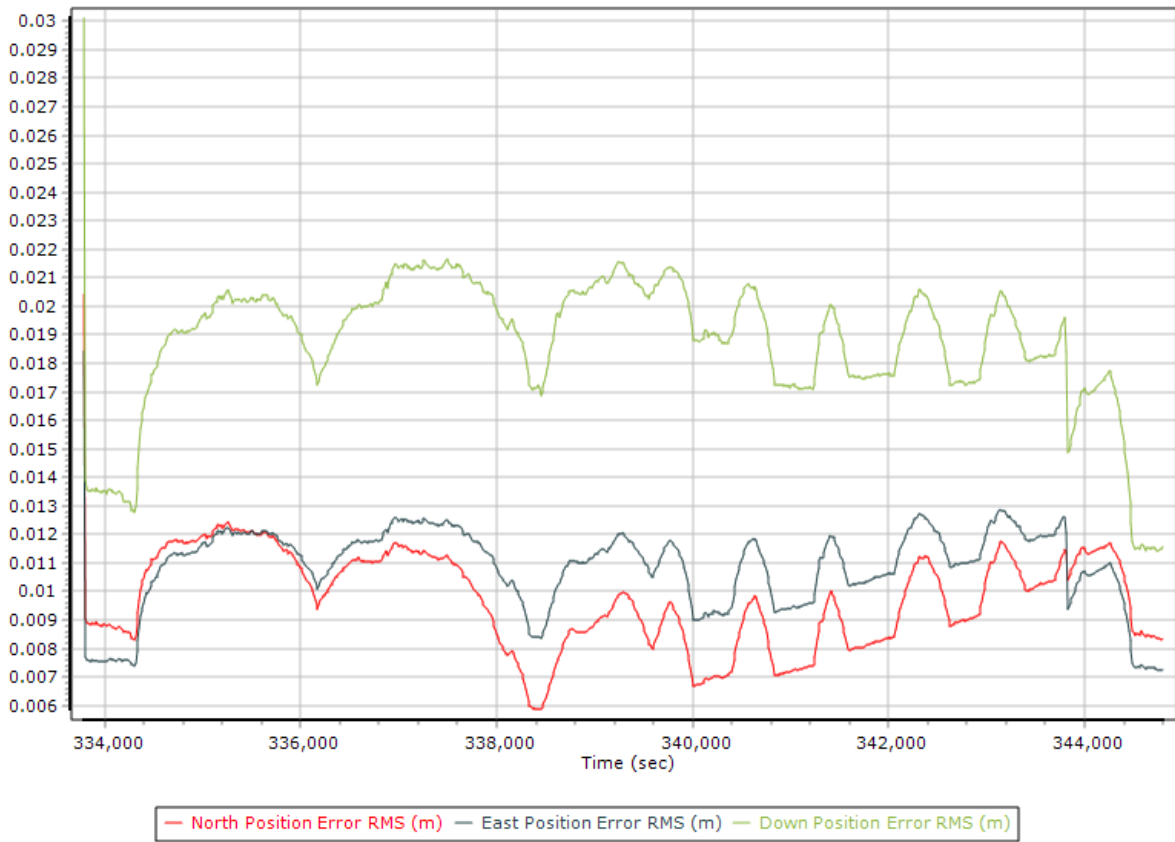
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

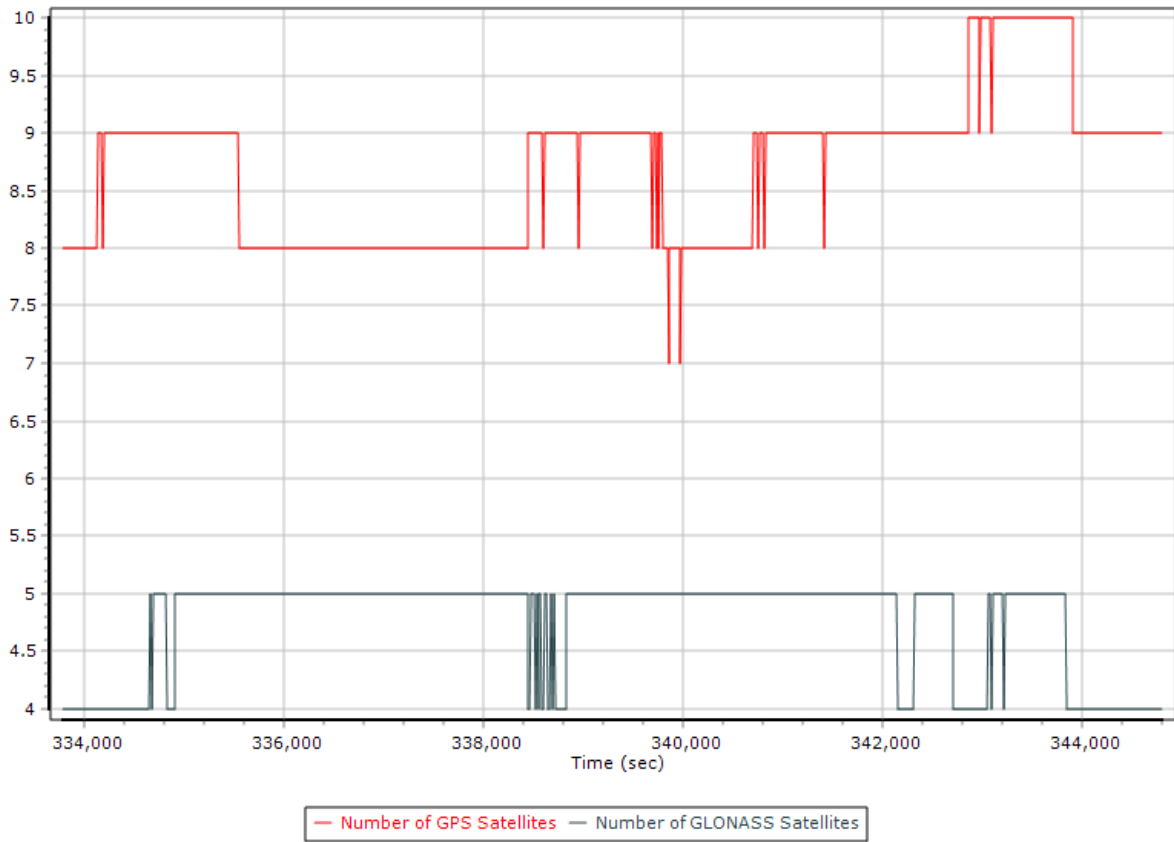


Processing mode



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





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

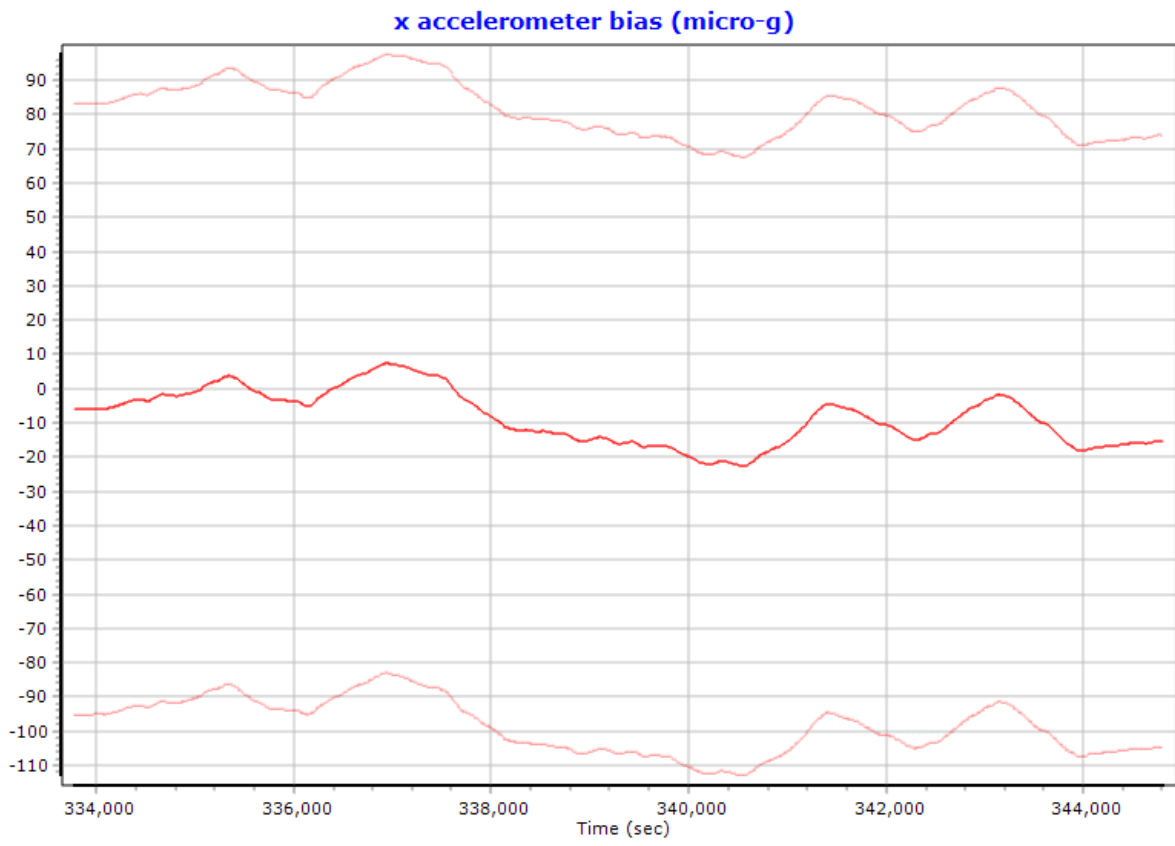
Start:

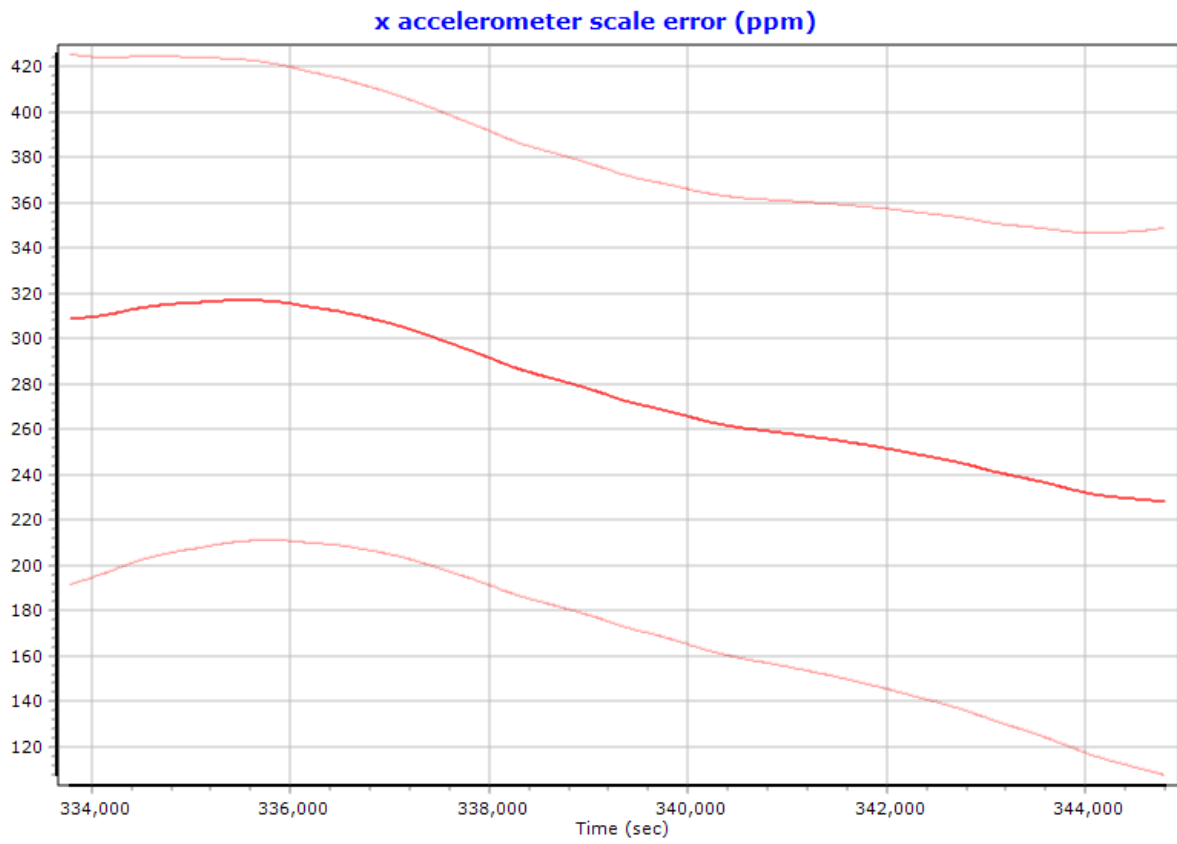
End:

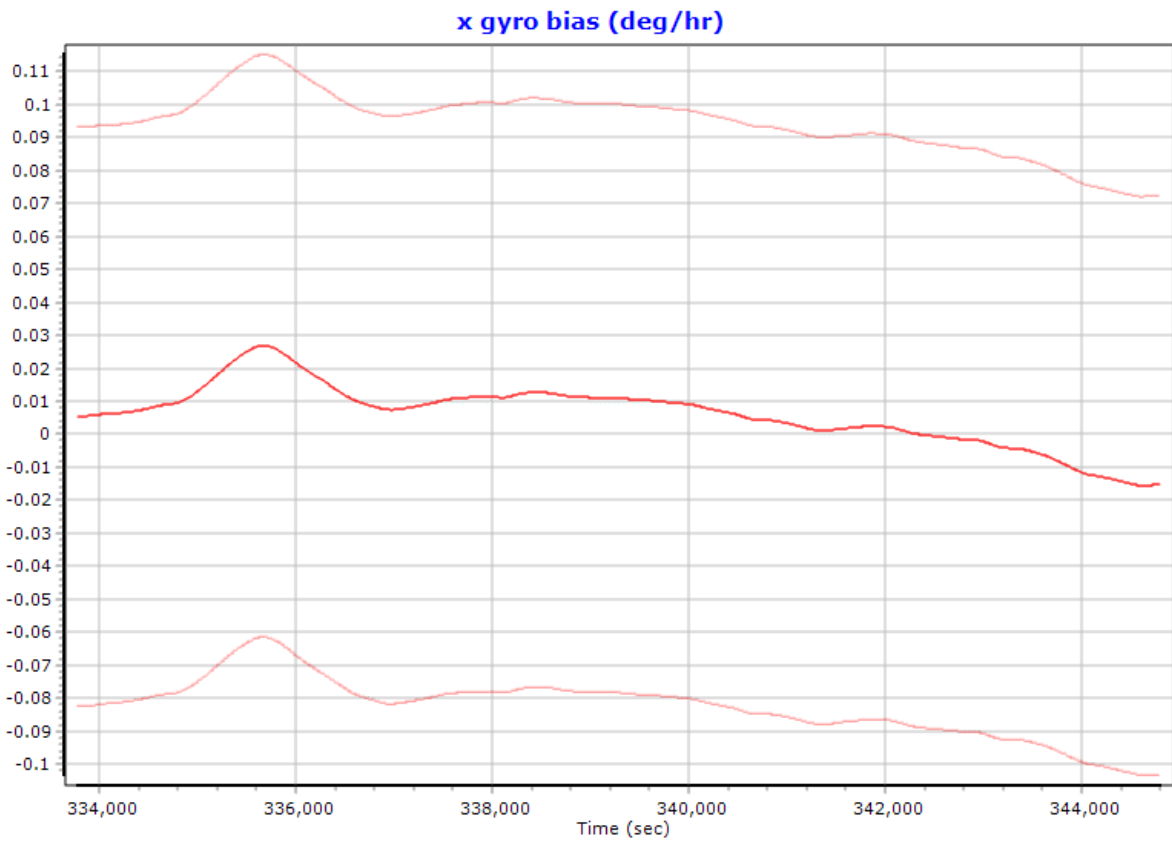
Entire time interval
 Seconds of start week

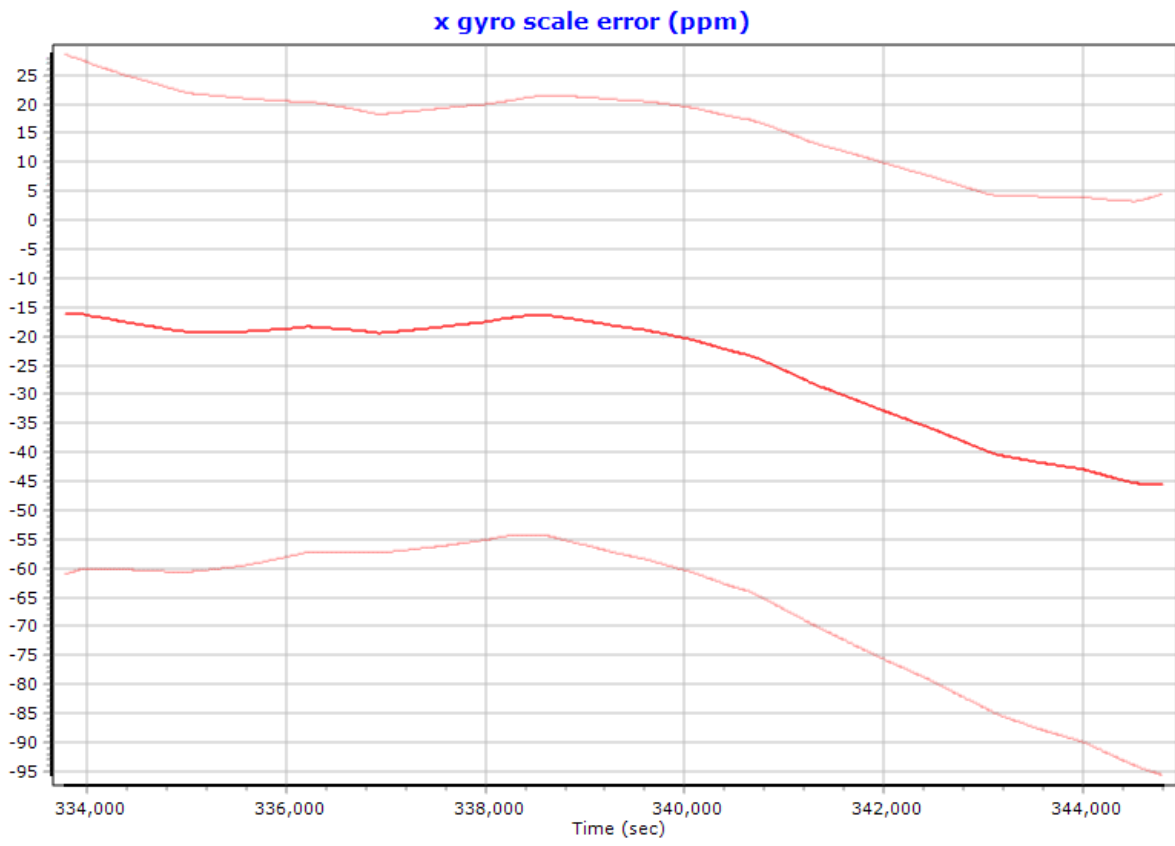
UTC Offset:

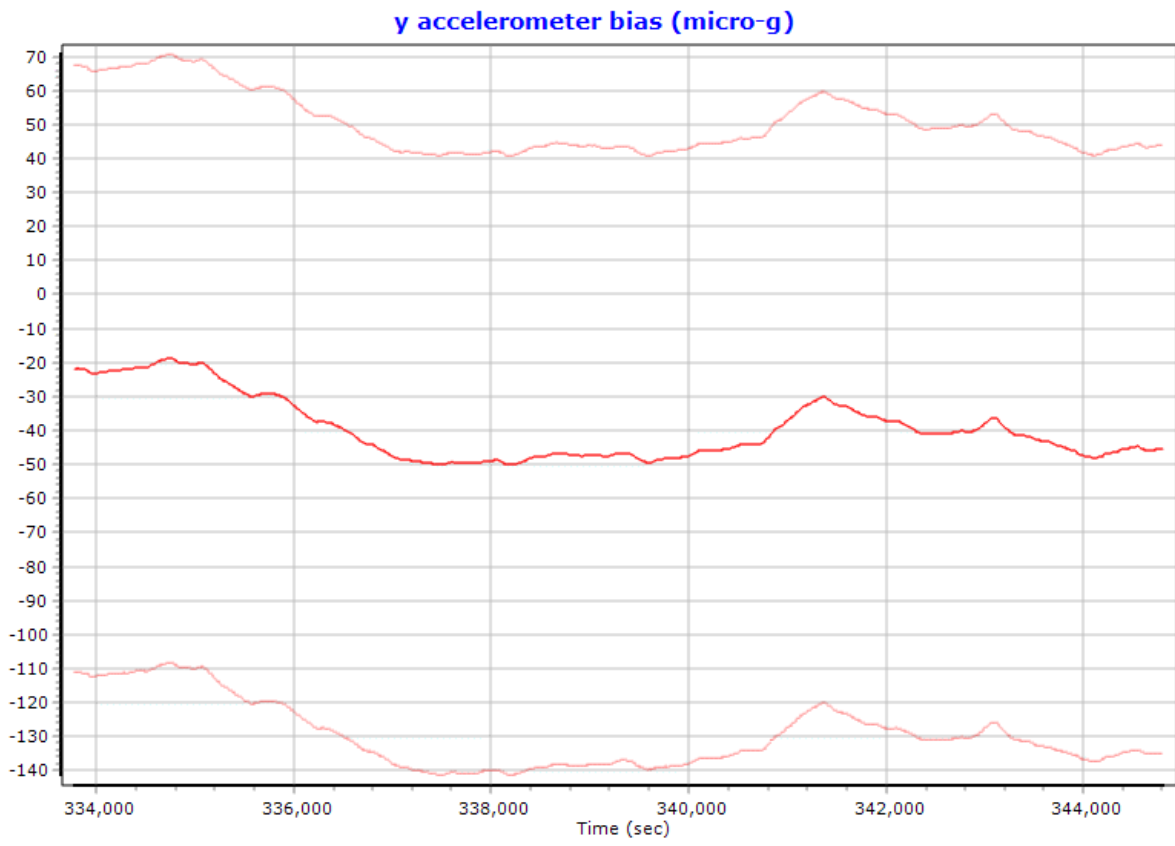
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

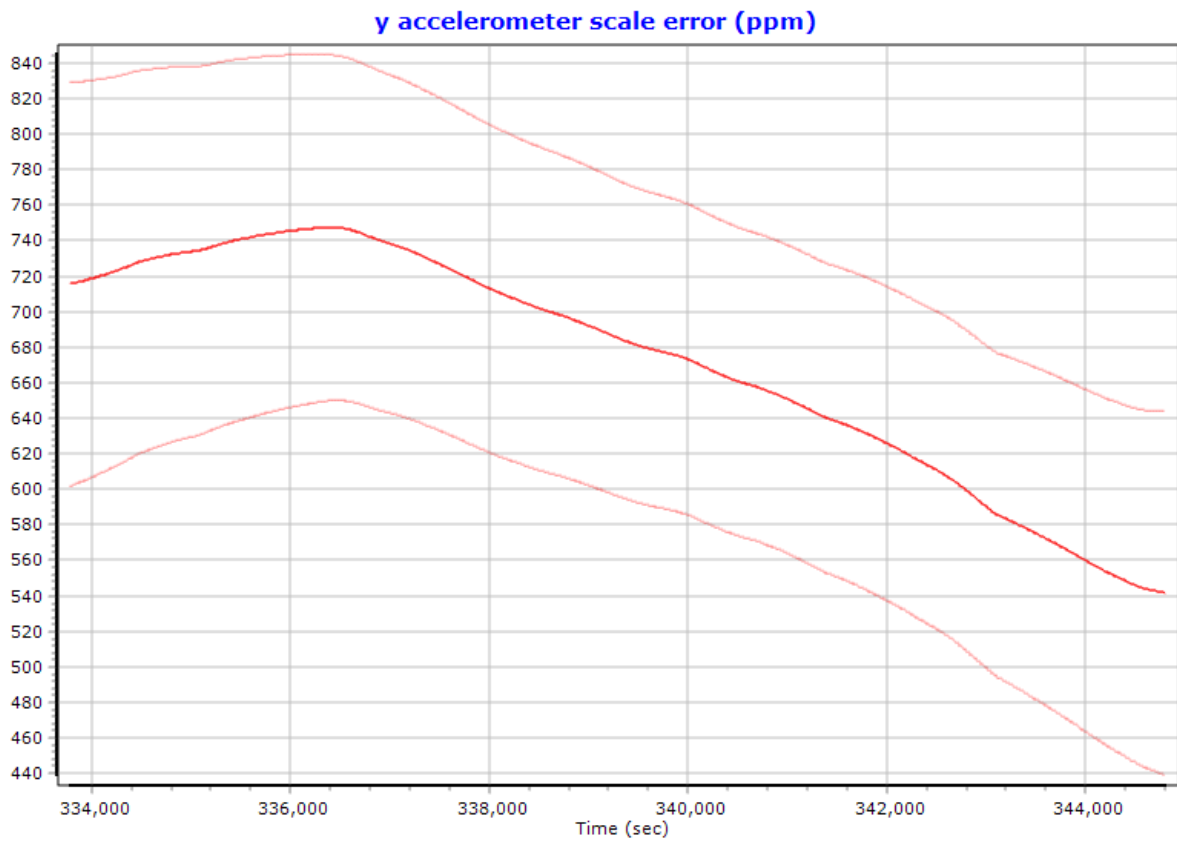


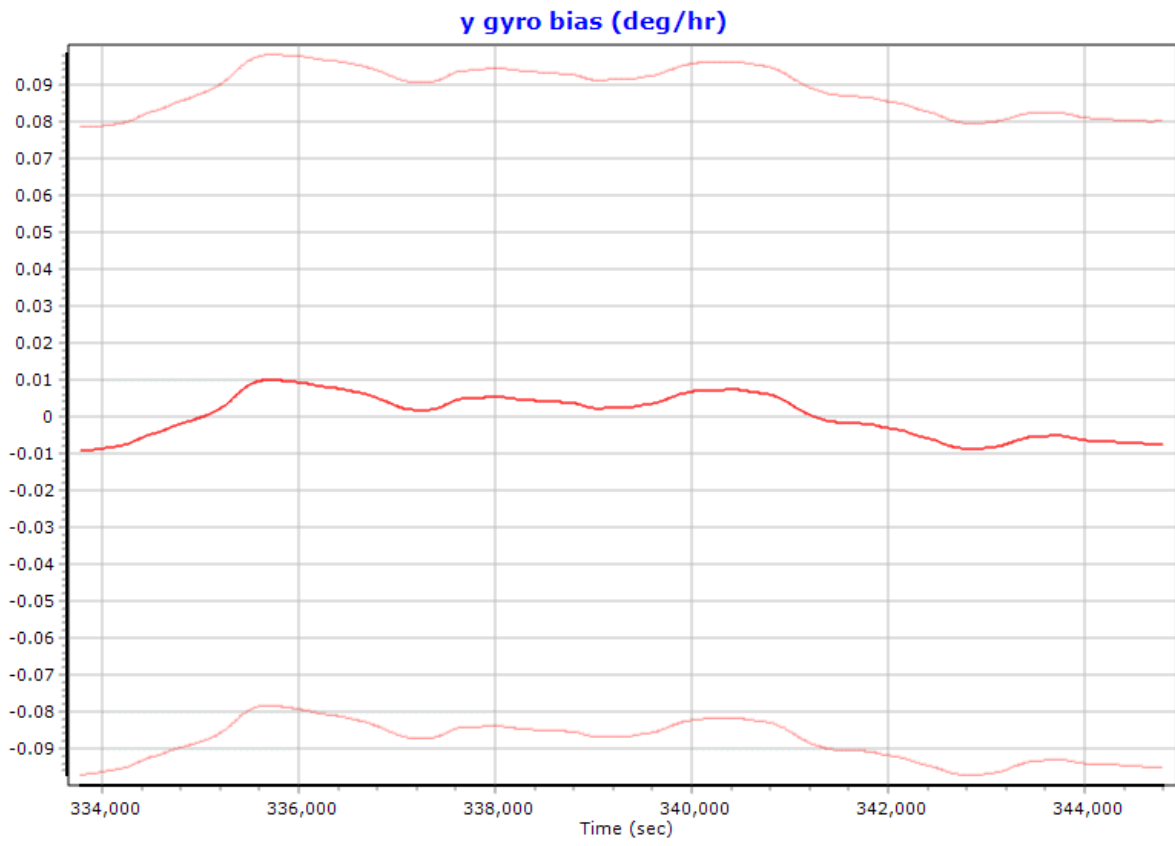


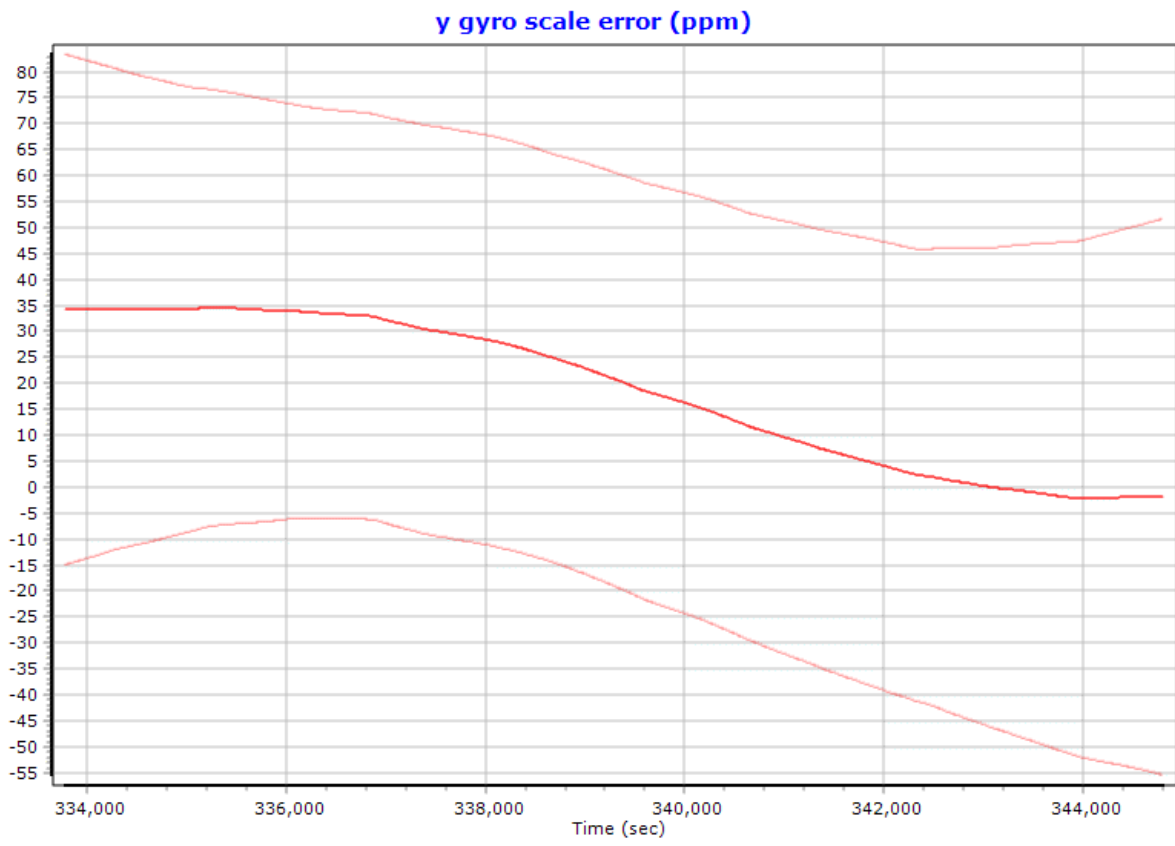


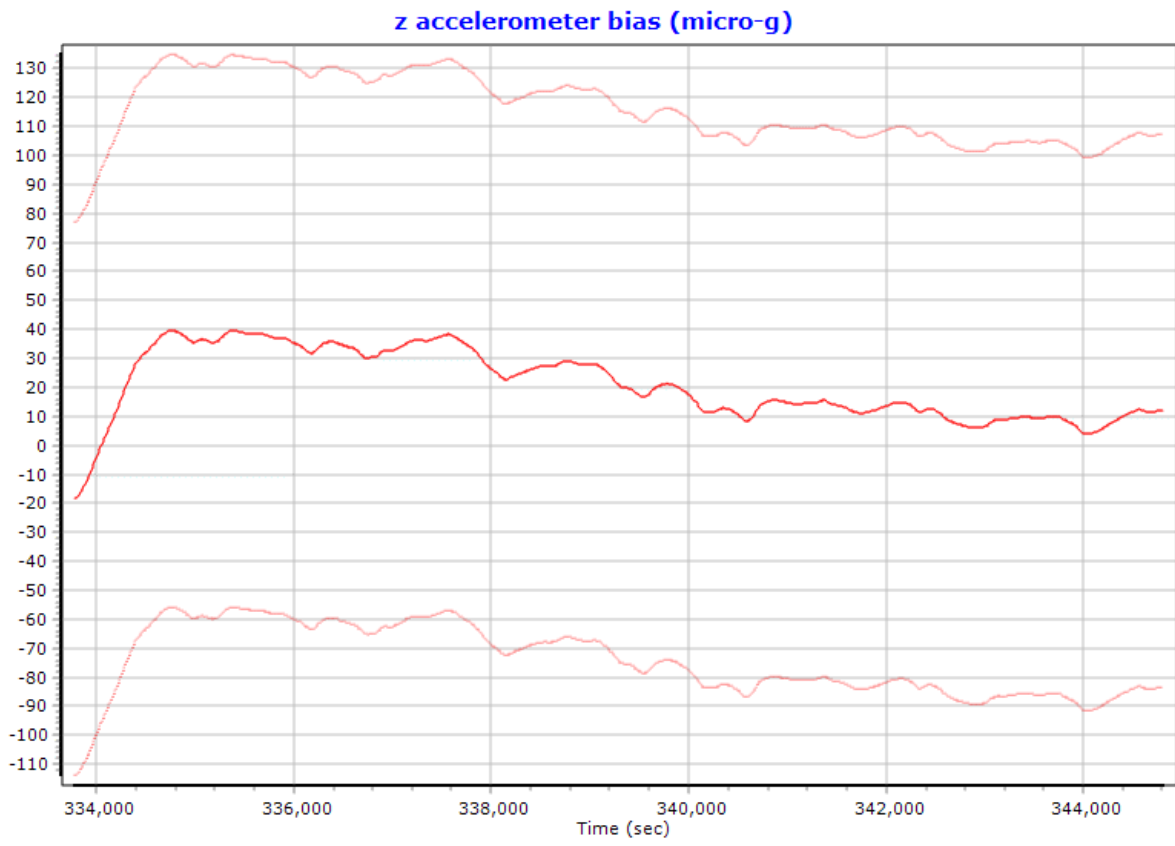


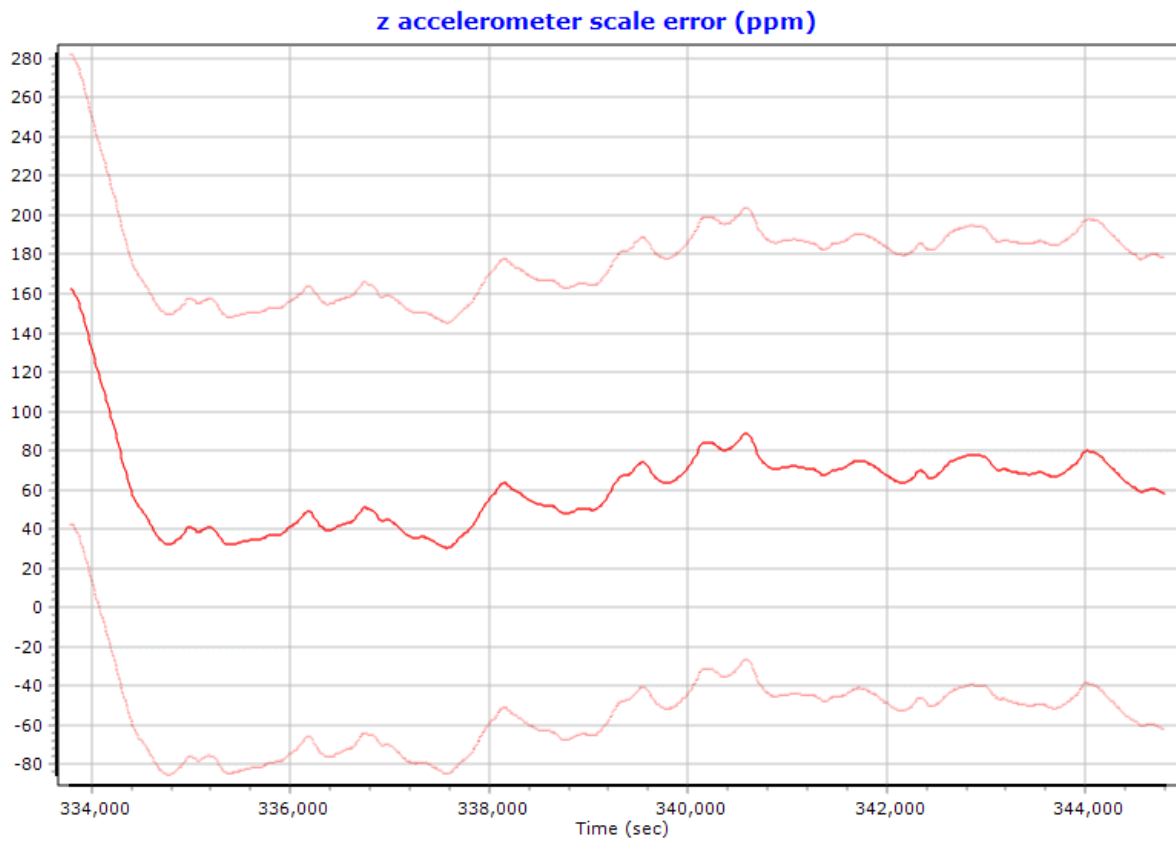


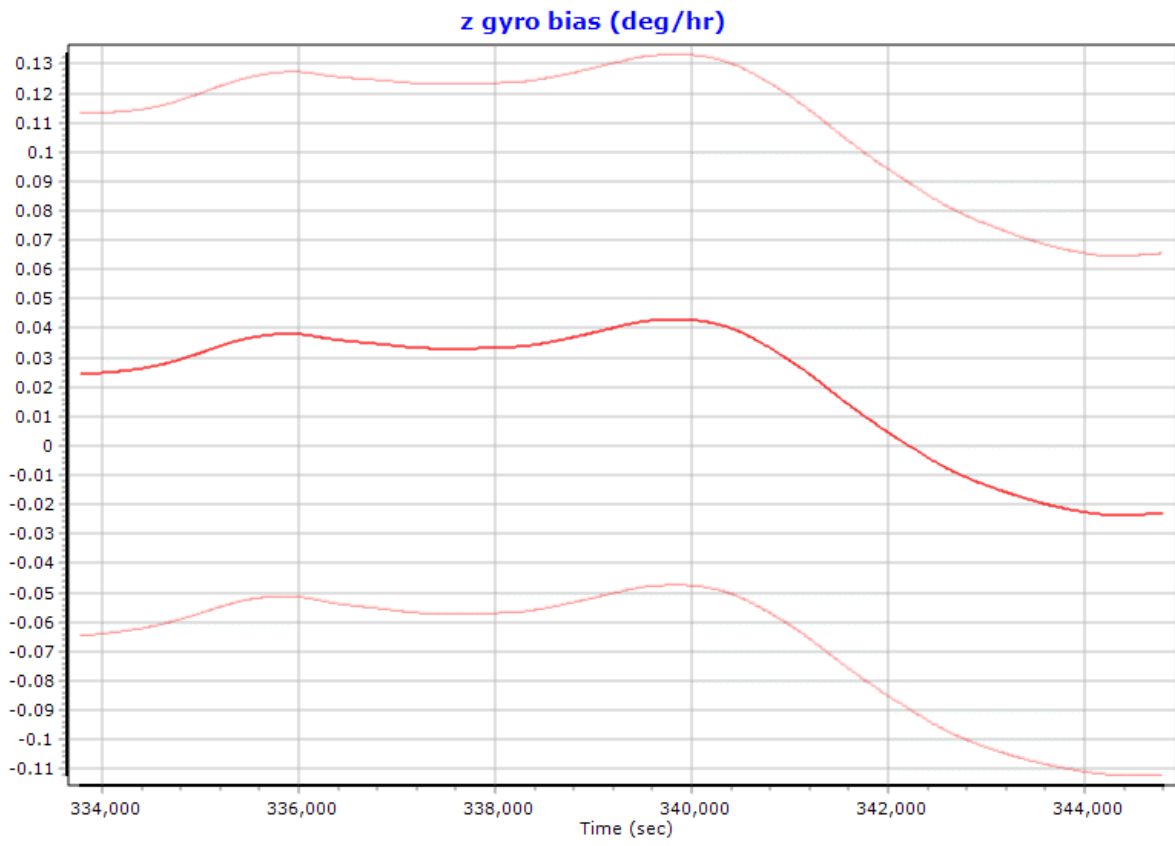


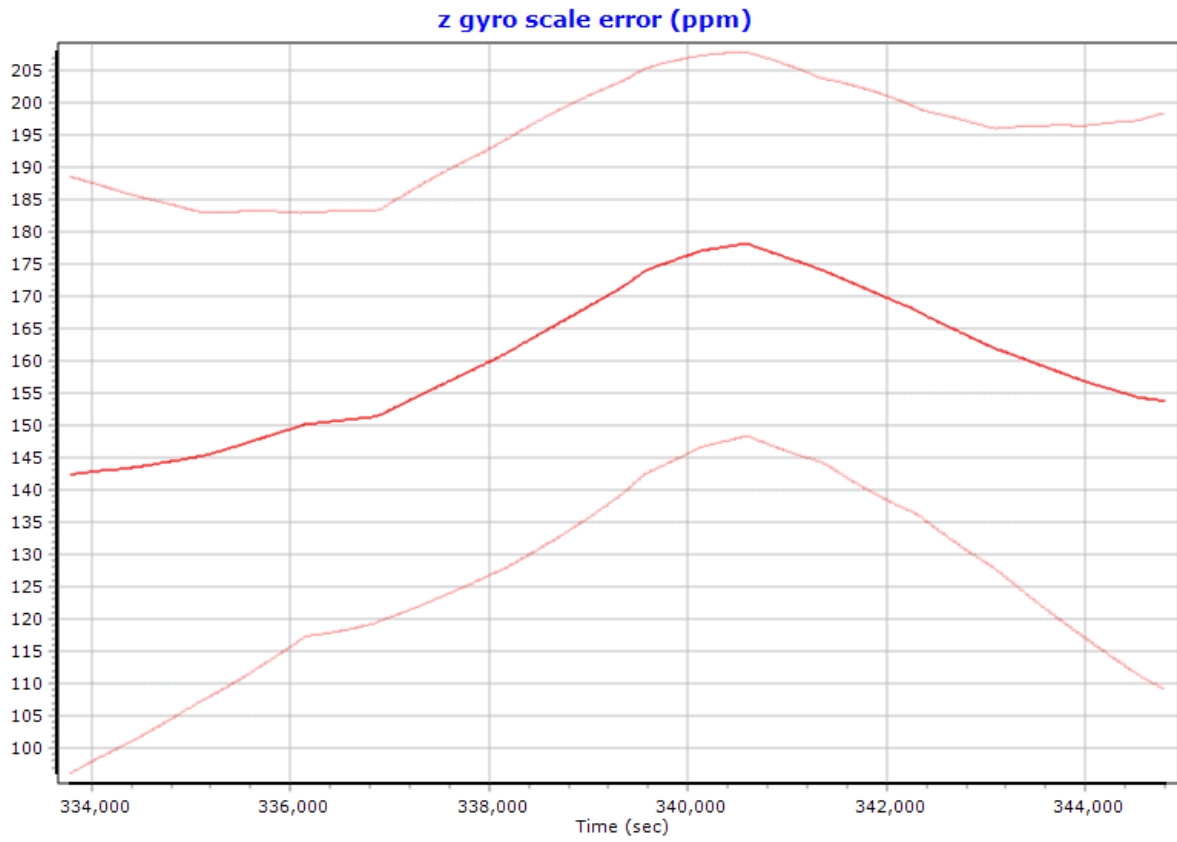




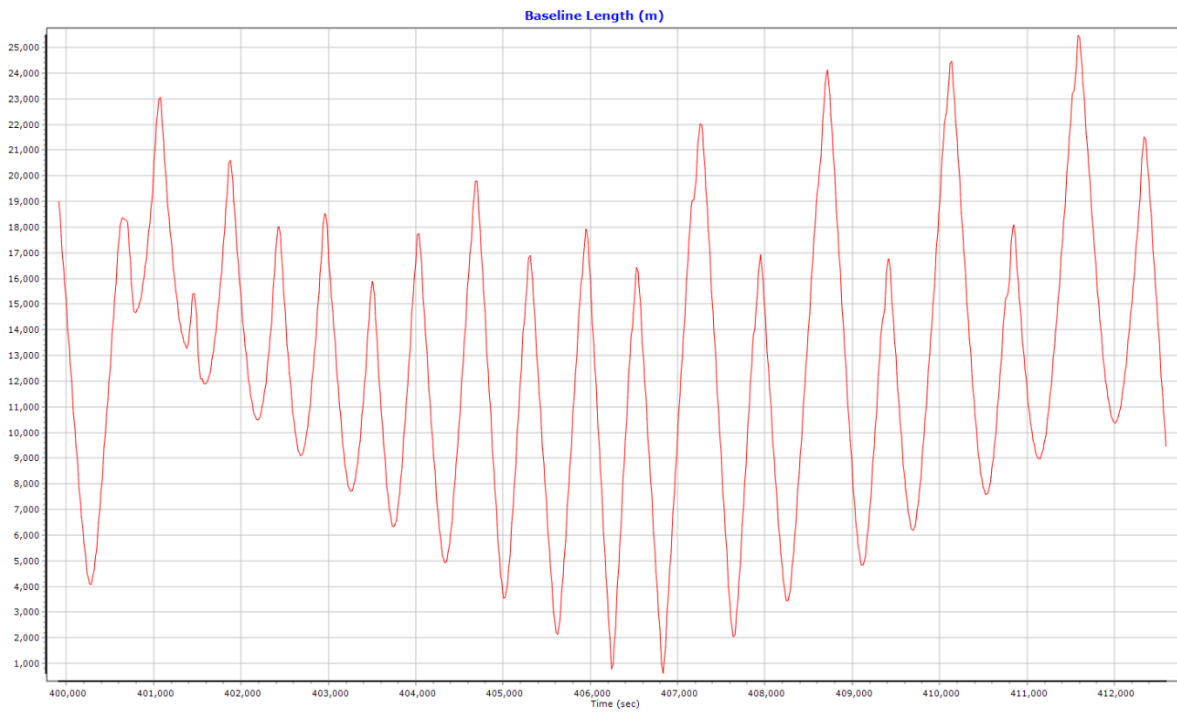
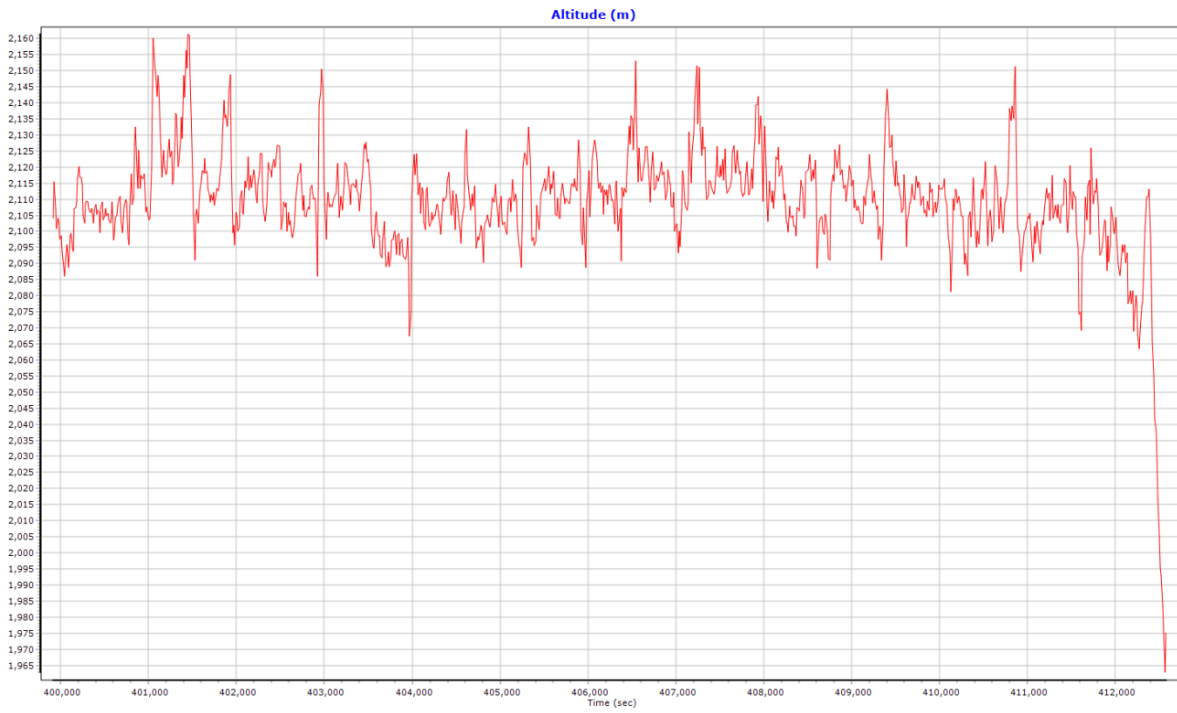


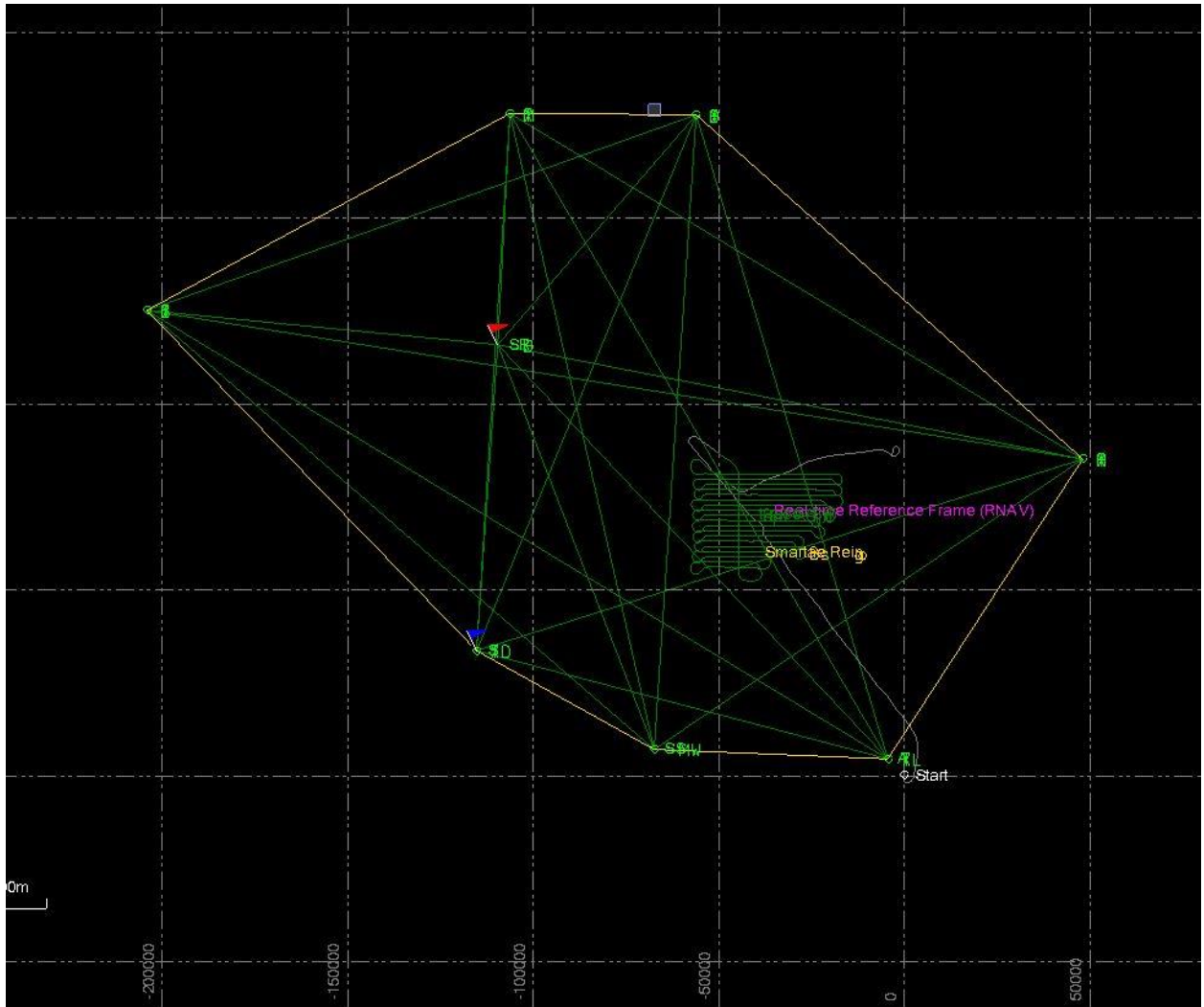






RBV18067A







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:

Standard Deviation: 10cm 50cm 1m 10m

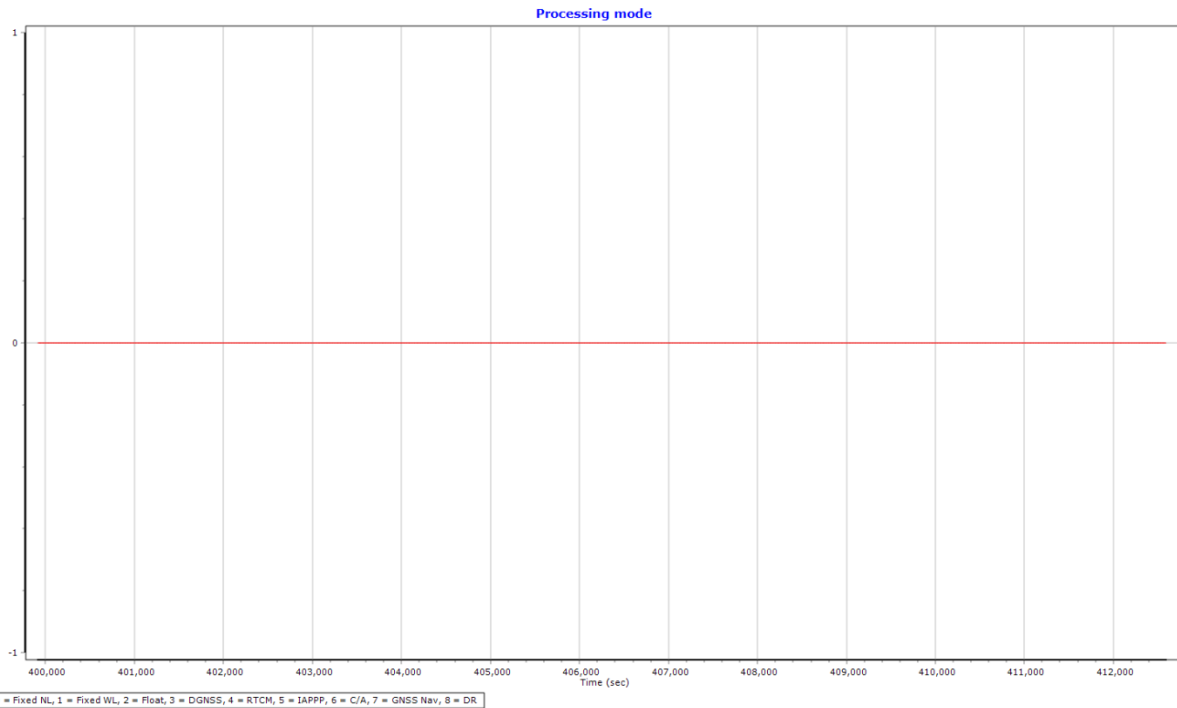
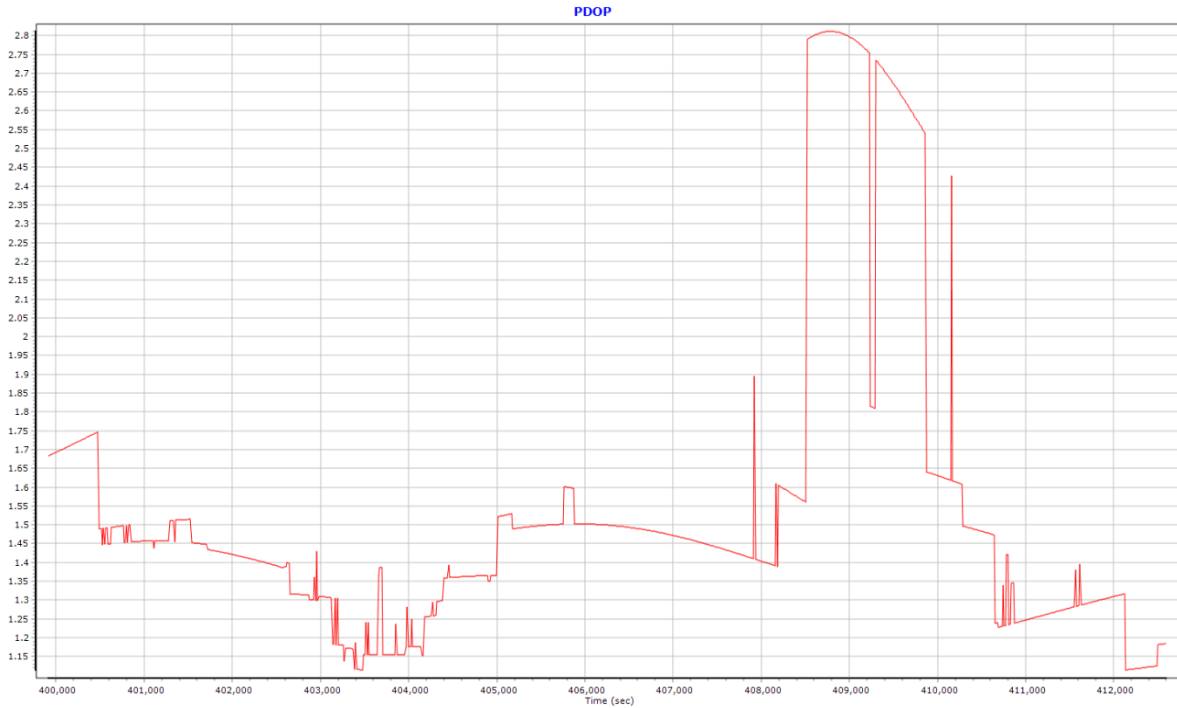
Aircraft to Stabilized Mount Mounting Angles

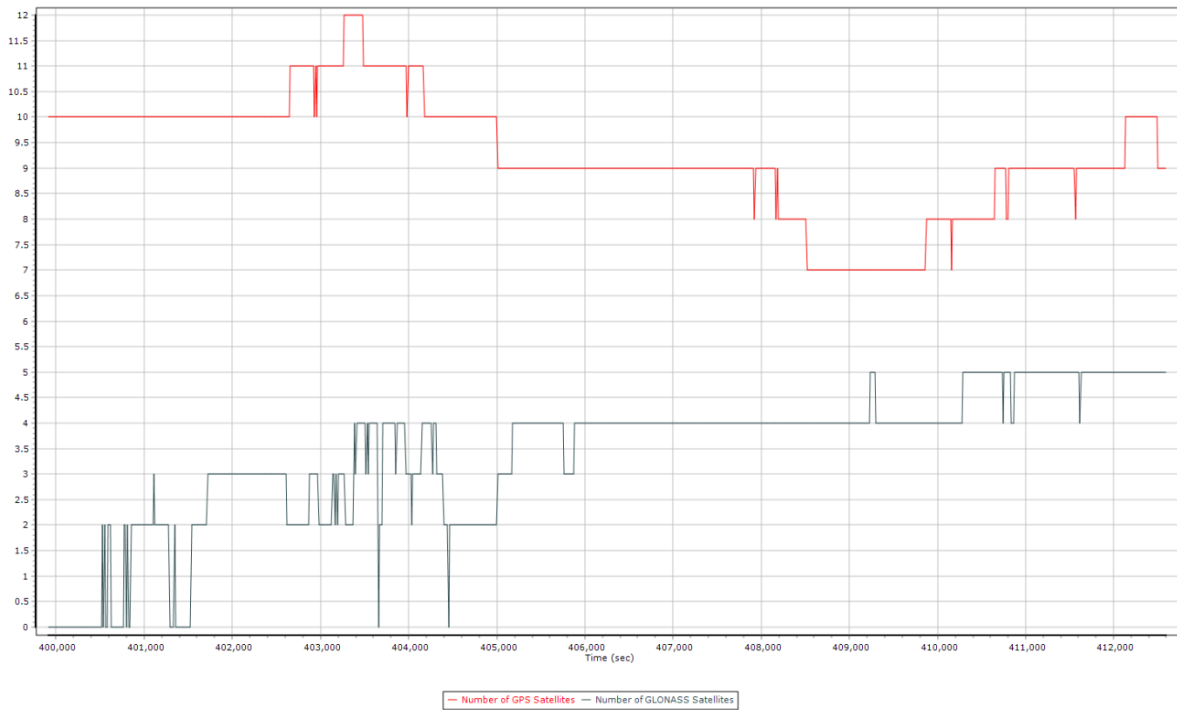
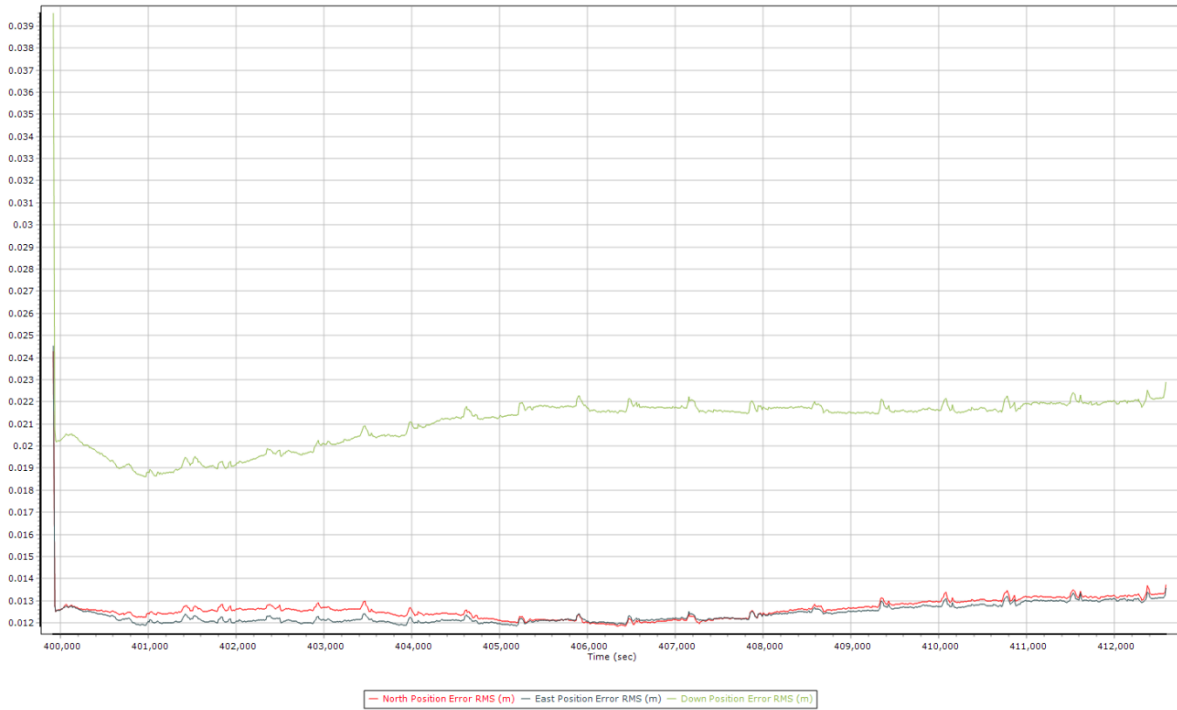
X:

Y:

Z:

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





Project Settings [X]

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

Timing

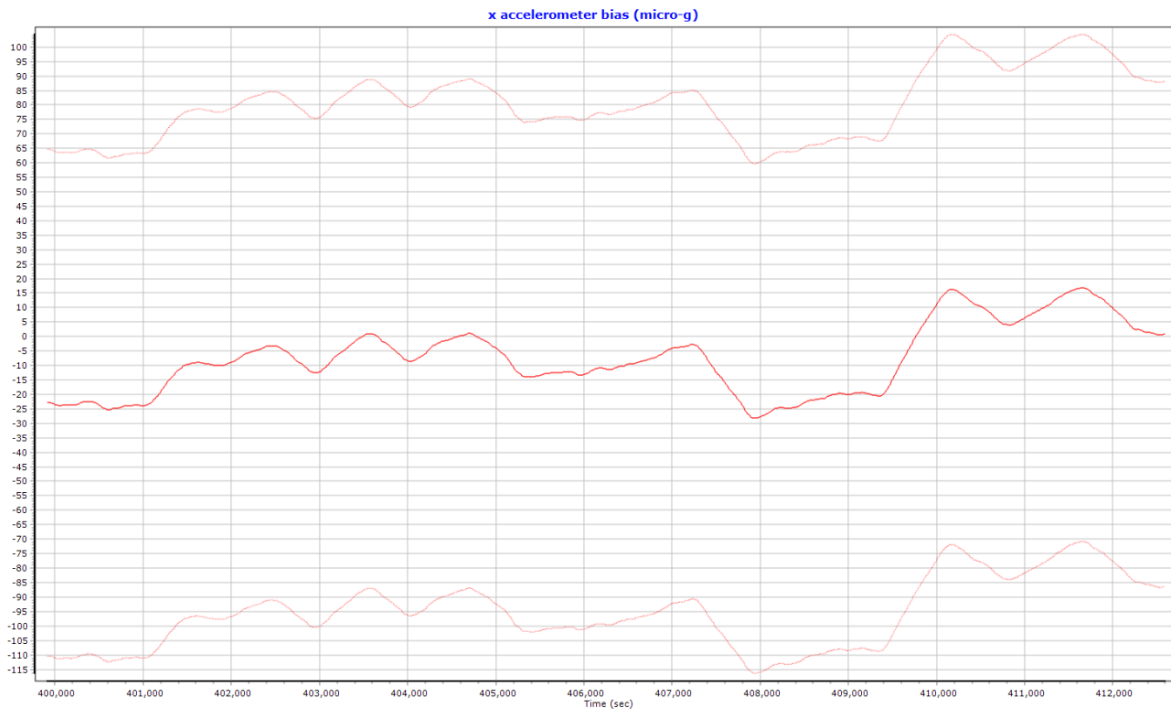
Start: 399912.123 End: 412601.040

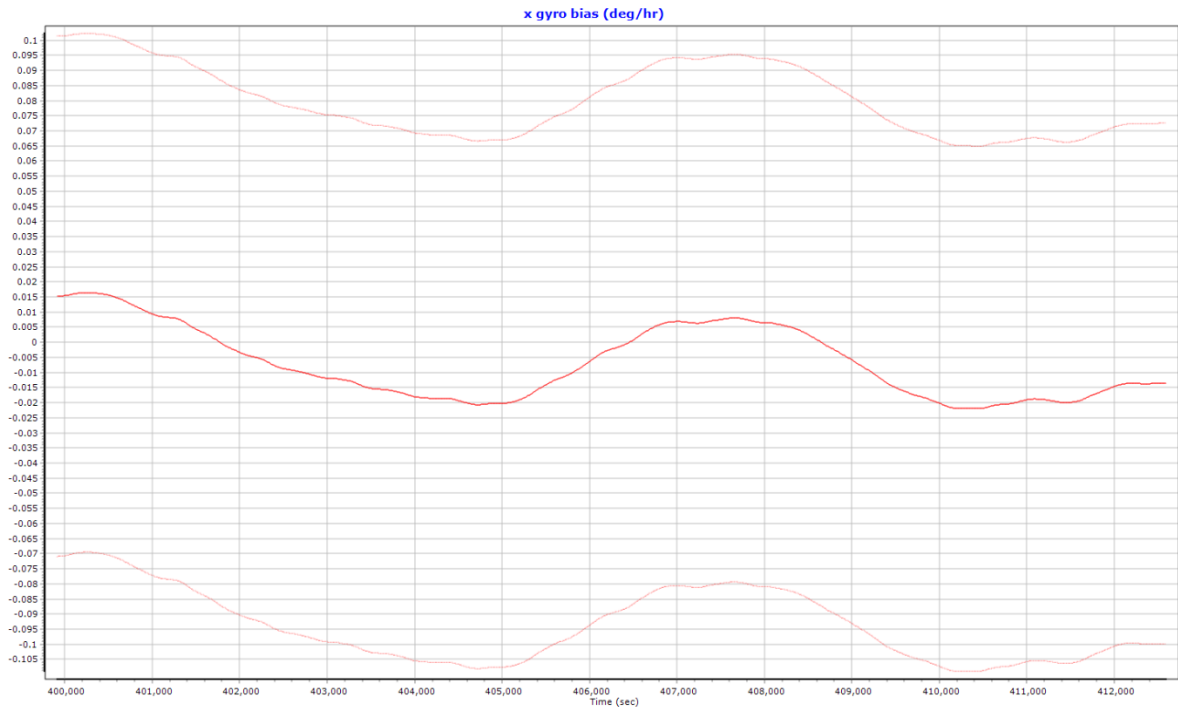
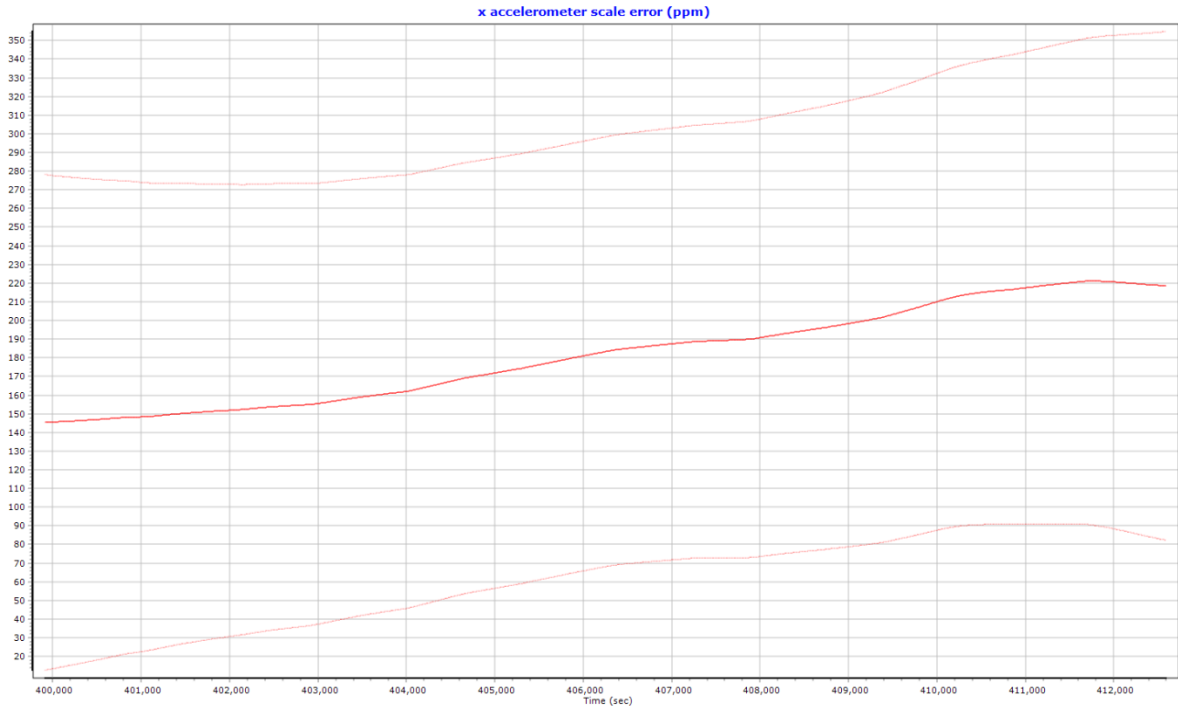
Entire time interval Seconds of start week

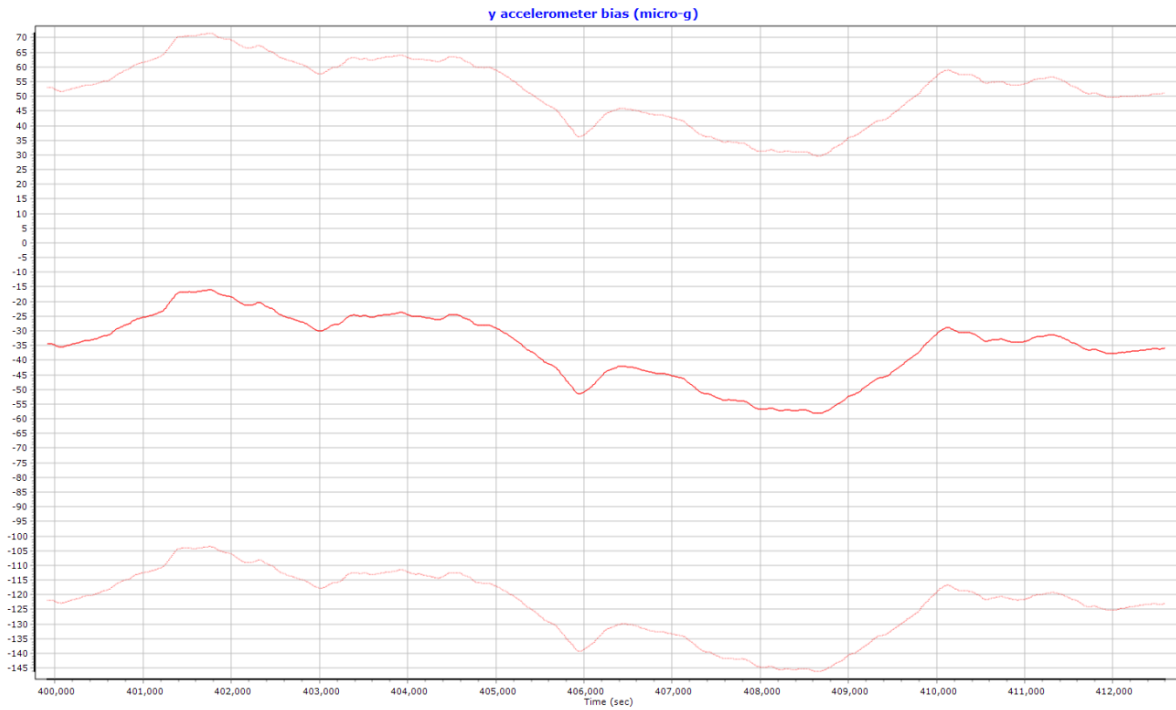
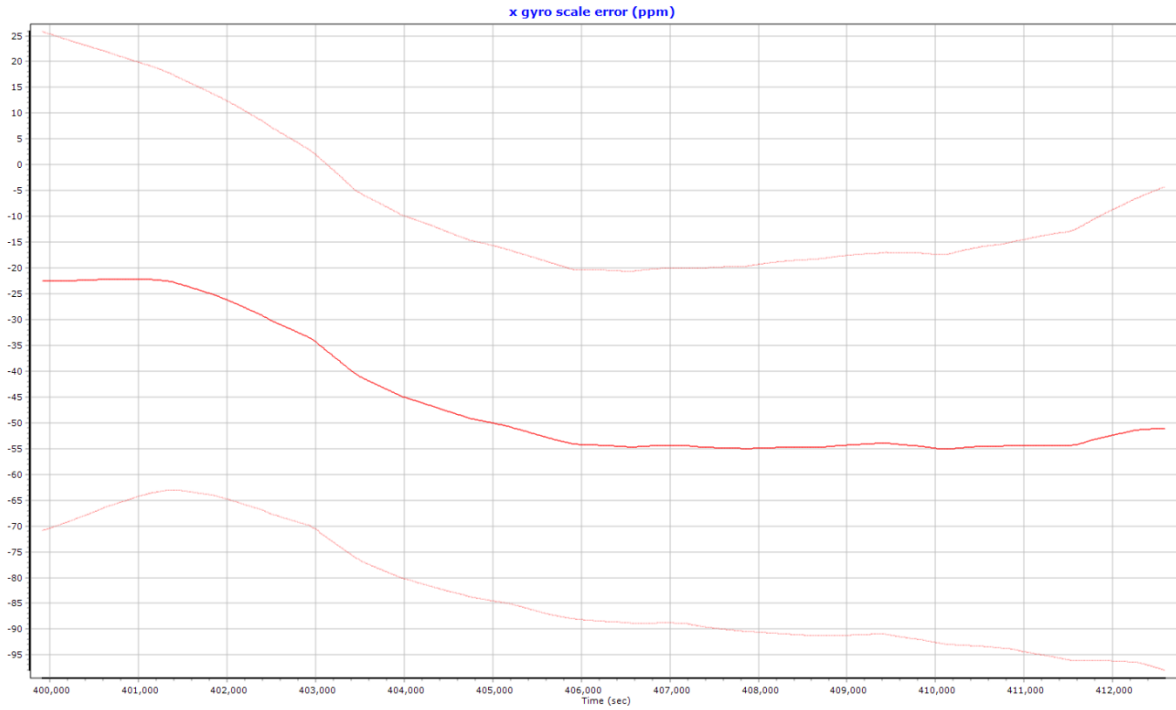
UTC Offset: 18.000

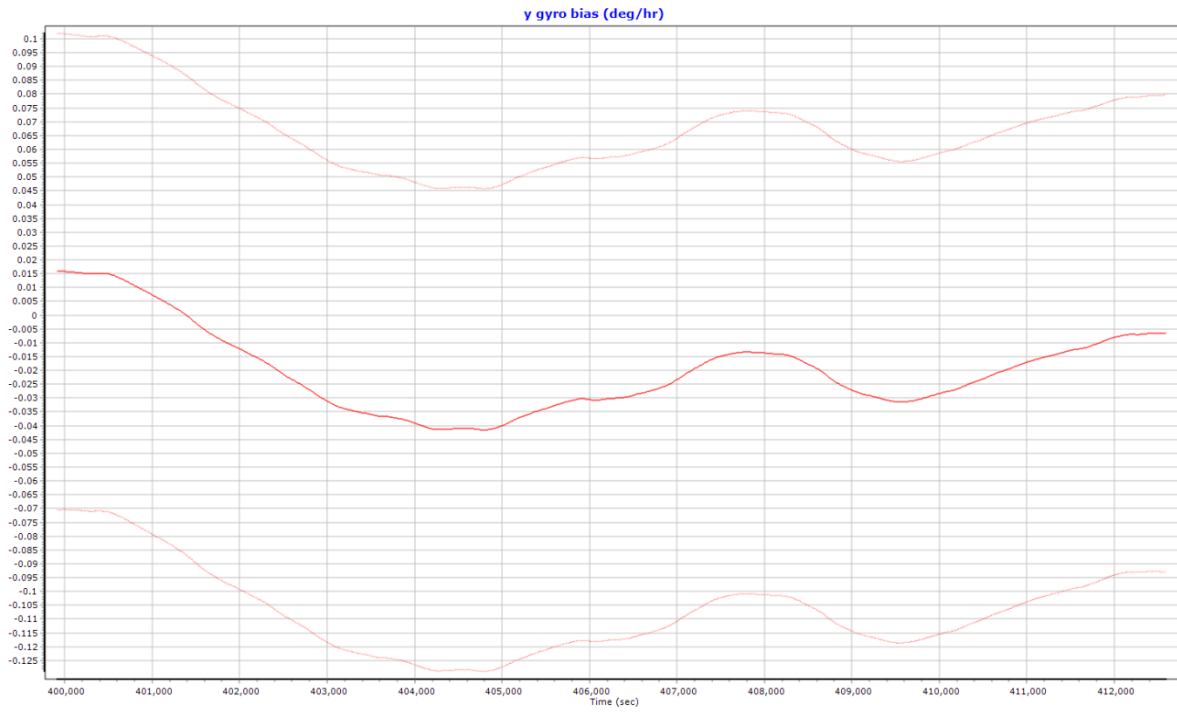
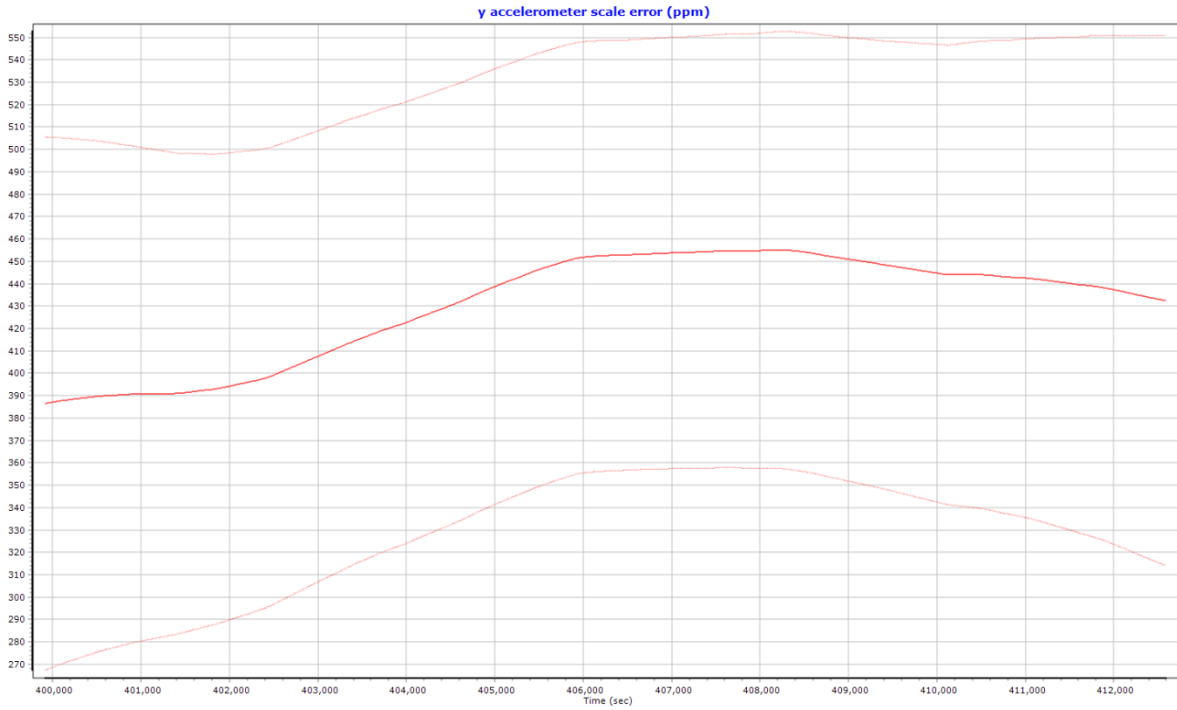
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

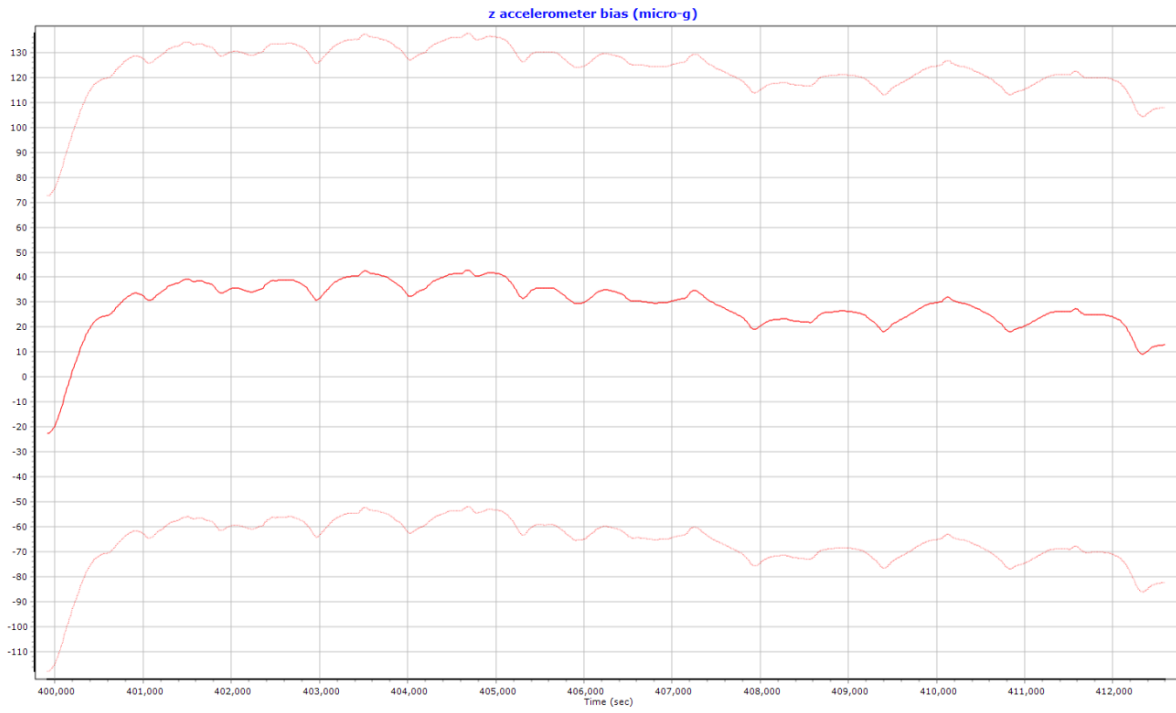
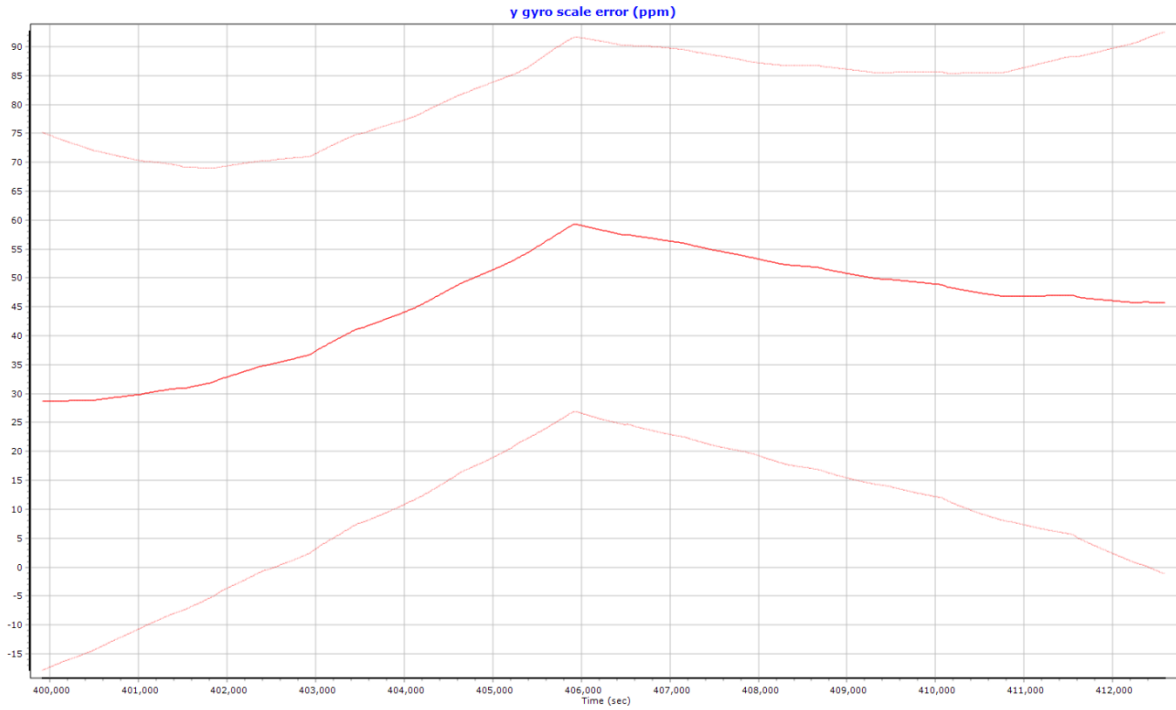
OK Cancel

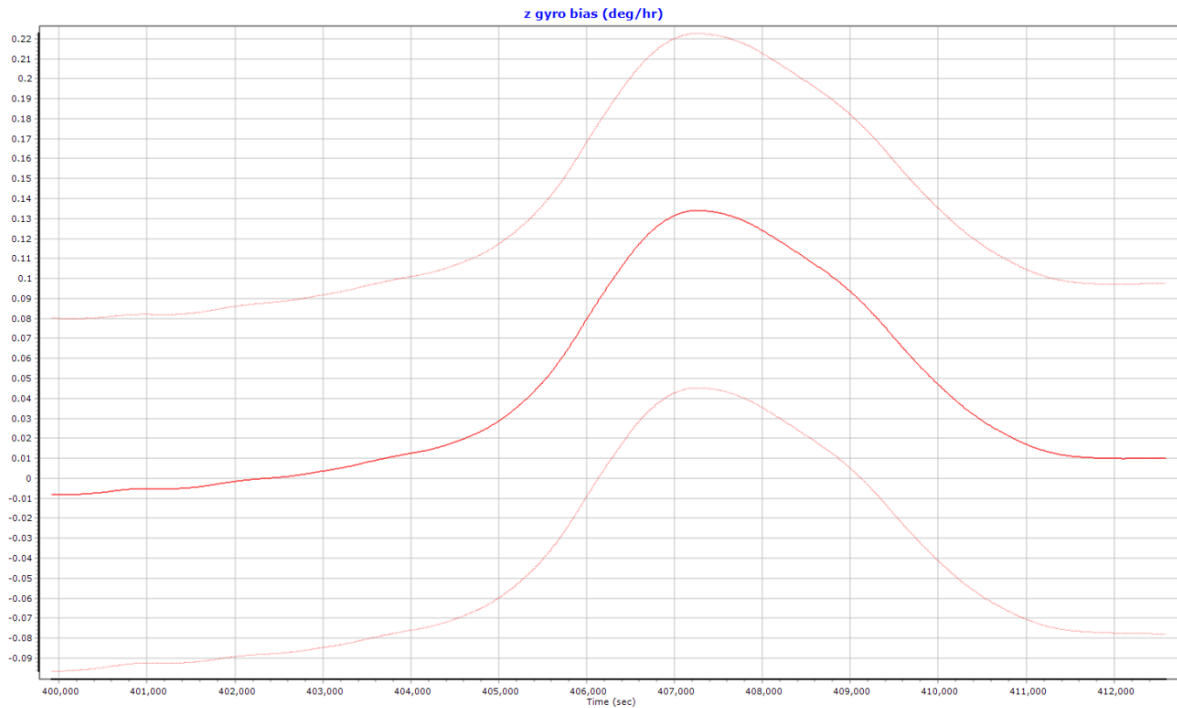
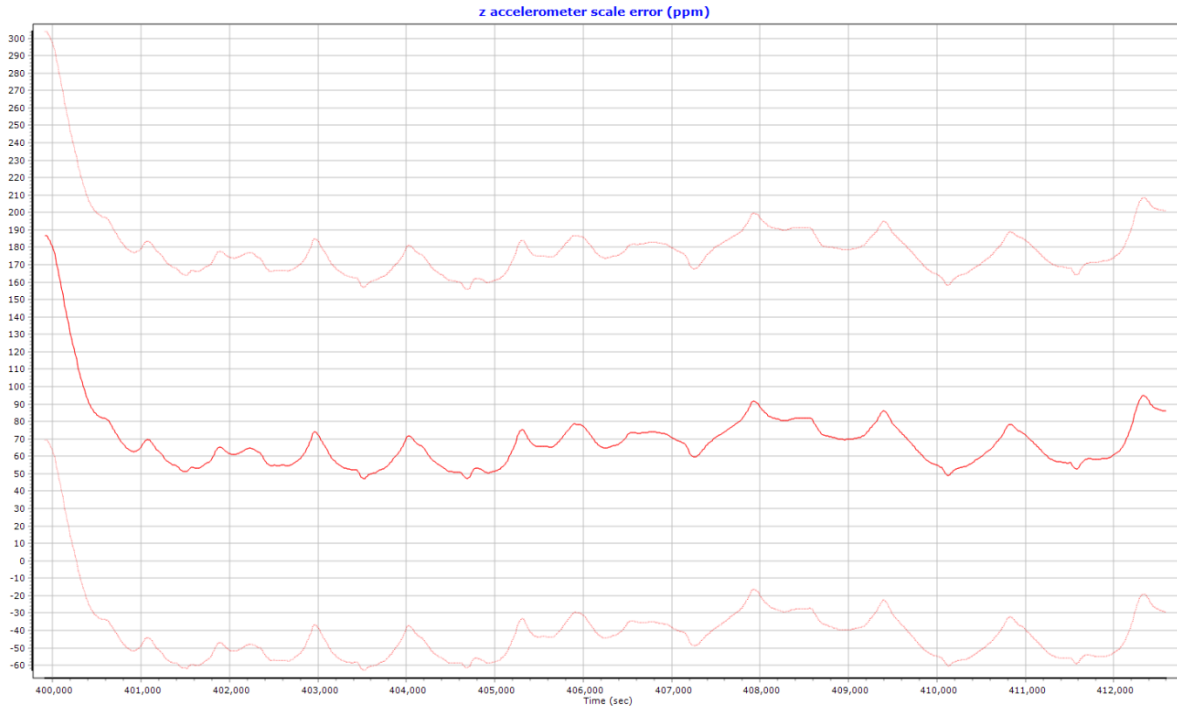


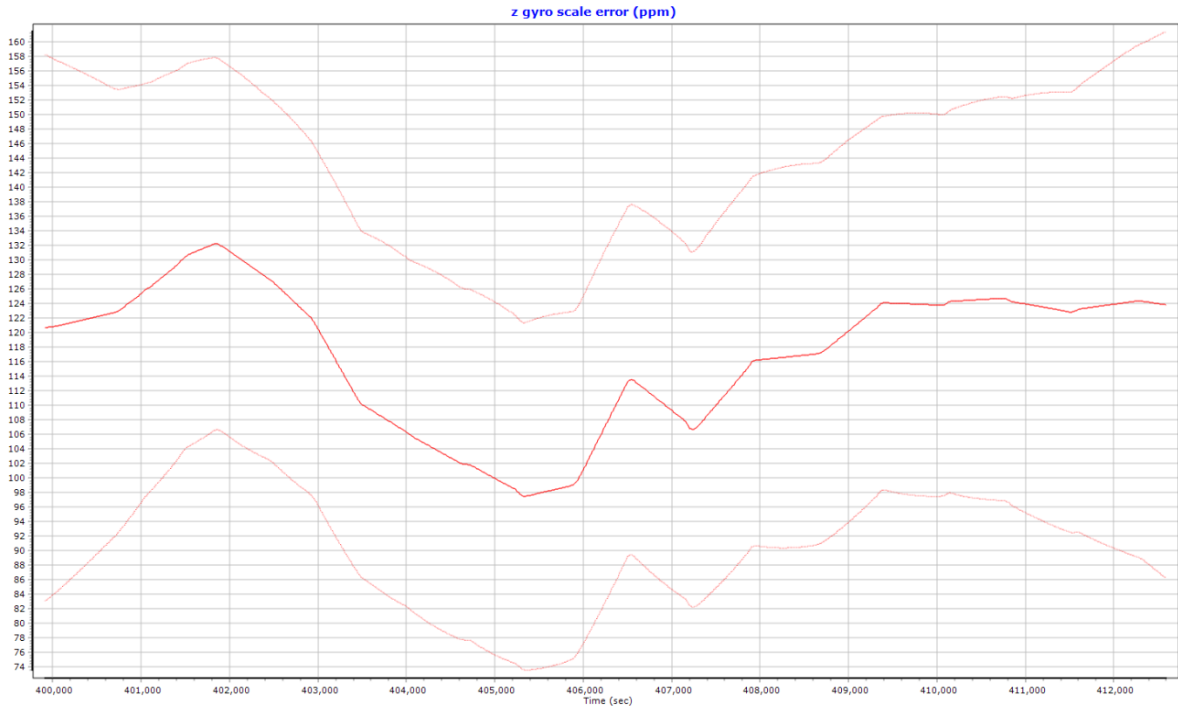




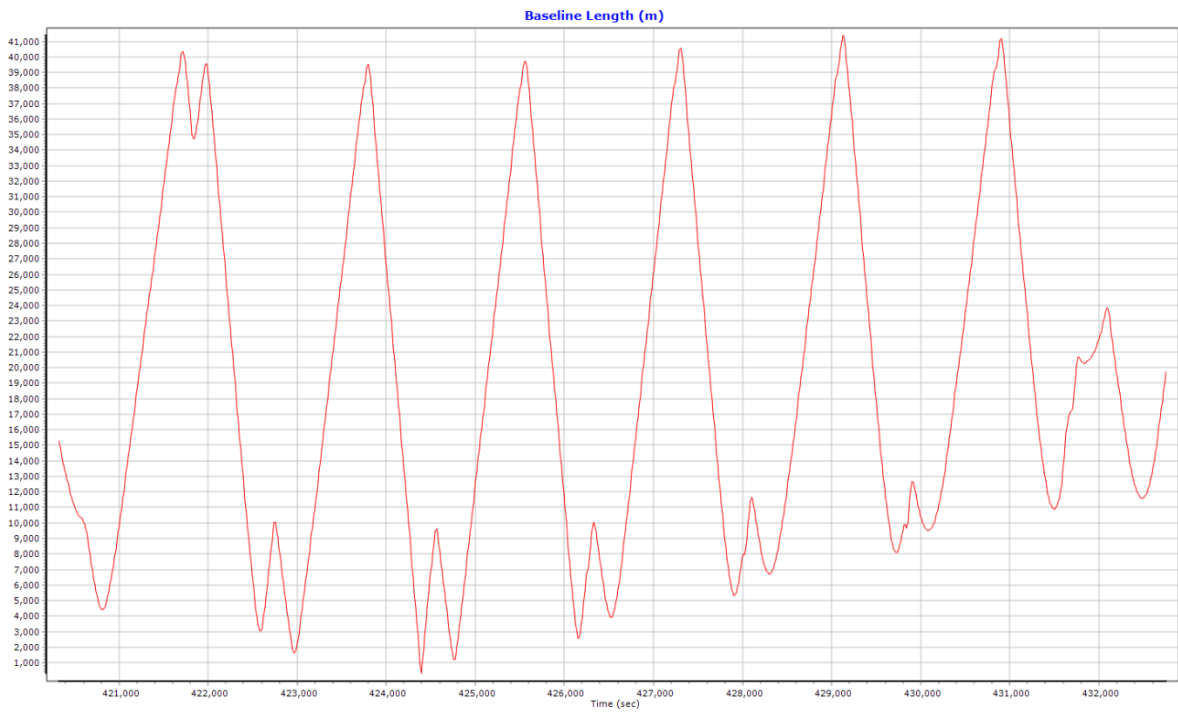
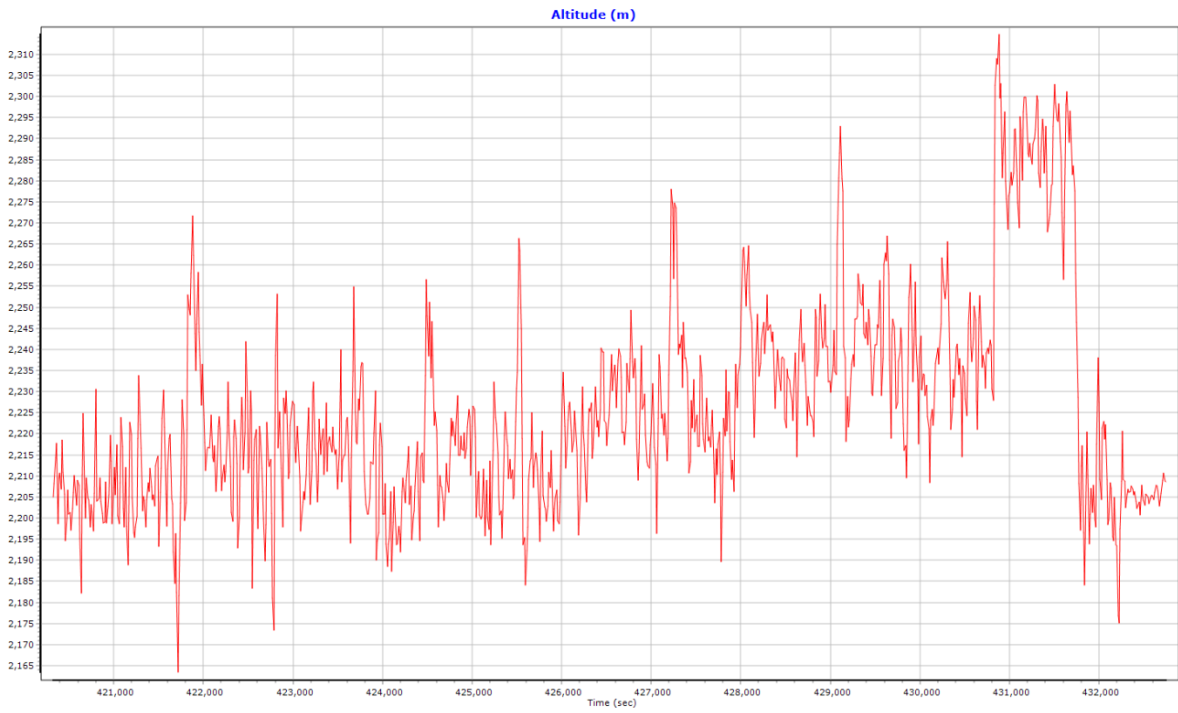


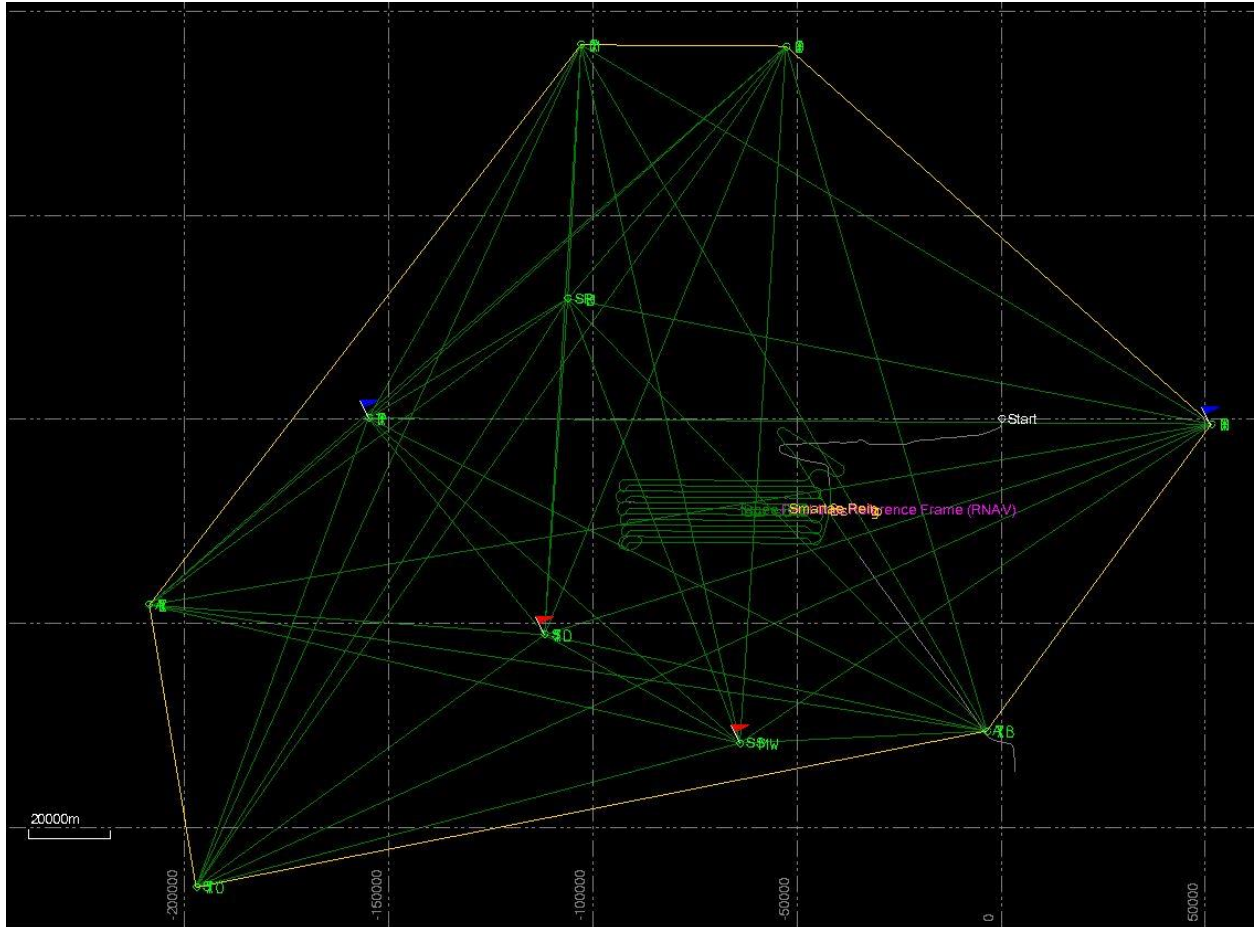






RBV18067B





Project Settings

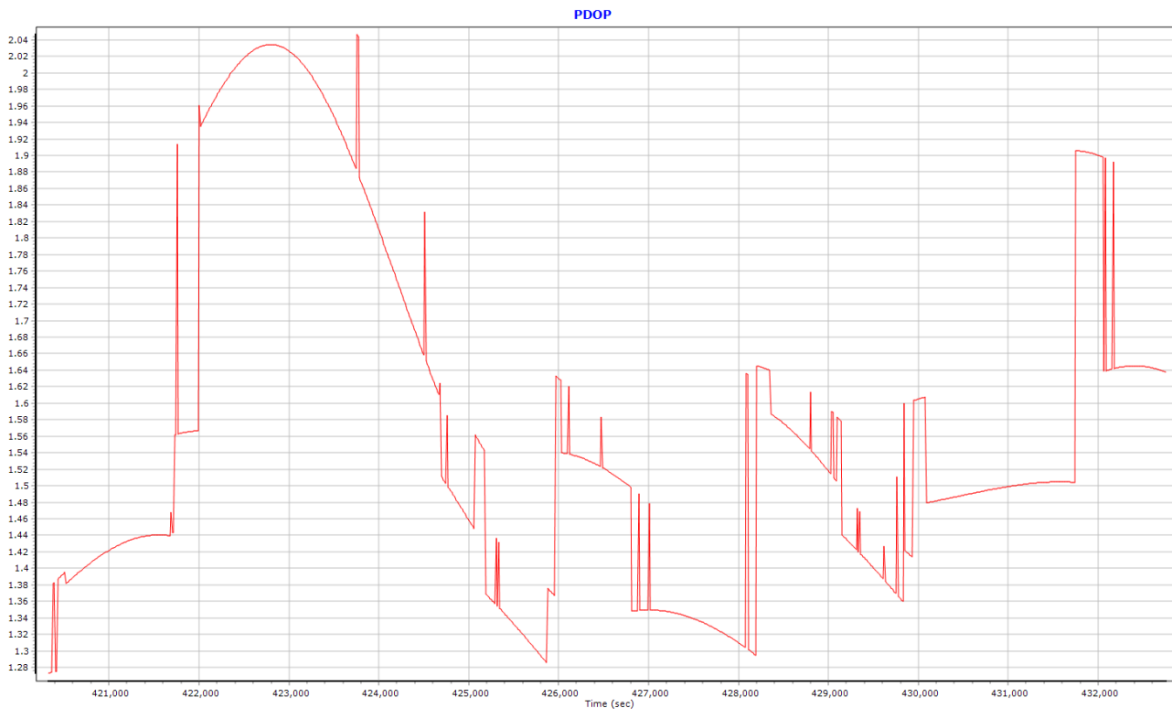
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

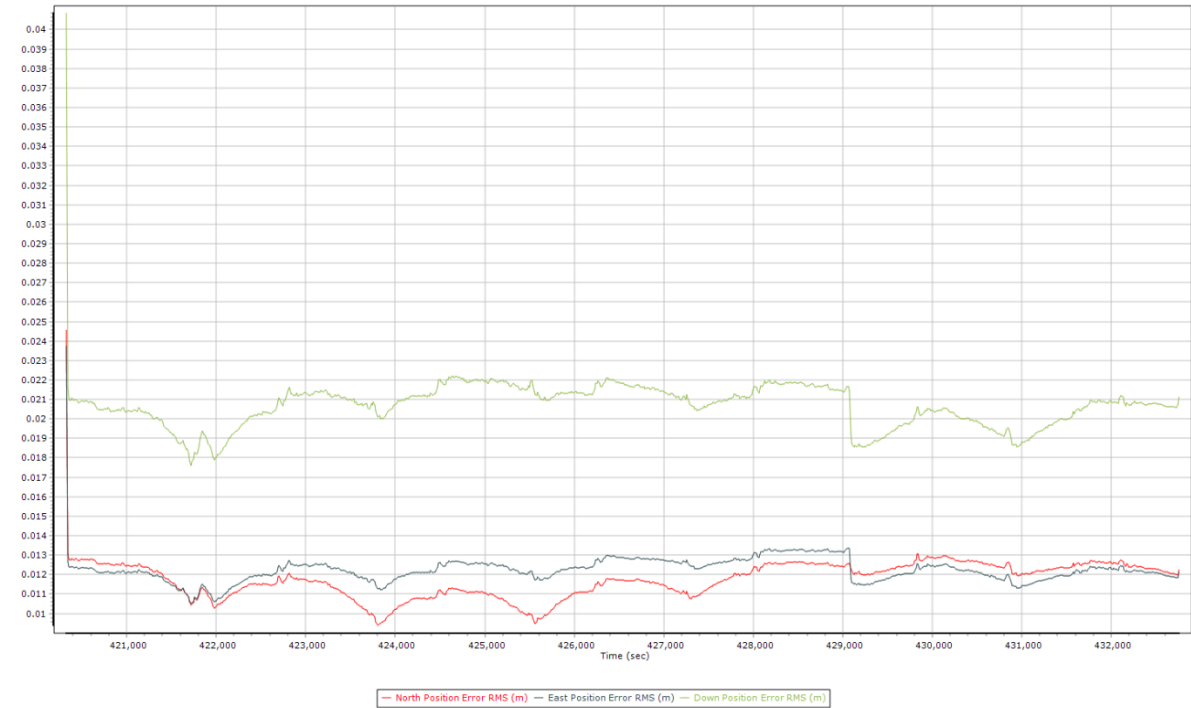
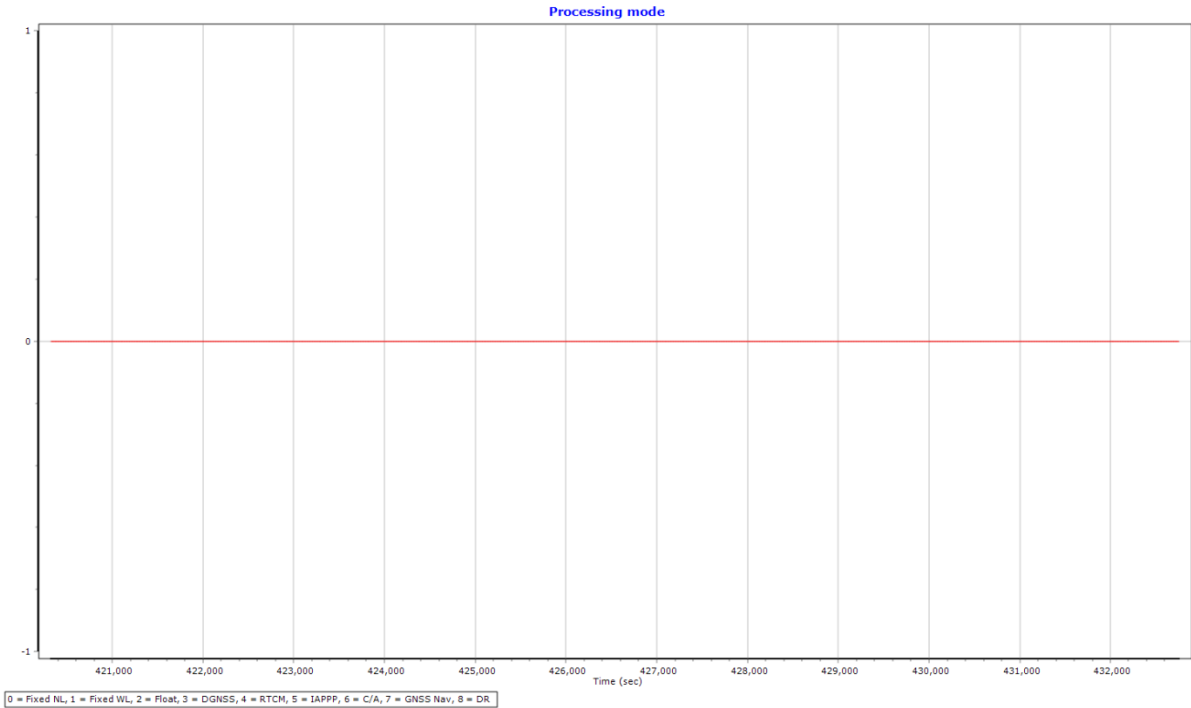
Category	X	Y	Z
Stabilized Mount to IMU Lever Arm	0.000 m	0.000 m	0.000 m
Stabilized Mount to IMU Mounting Angles	0.000 deg	0.000 deg	0.000 deg
Stabilized Mount to Primary GNSS Lever Arm	-0.031 m	0.004 m	-0.611 m
Aircraft to Stabilized Mount Mounting Angles	0.000 deg	0.000 deg	0.000 deg

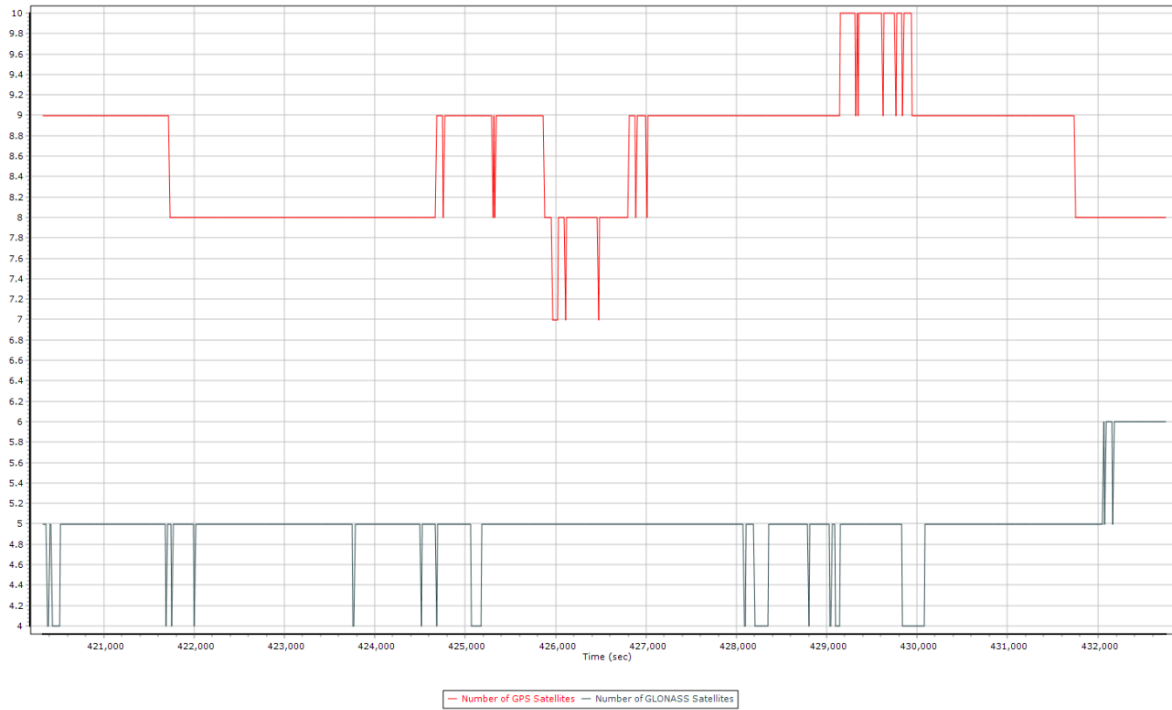
Standard Deviation: <3cm 10cm 50cm 1m 10m

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

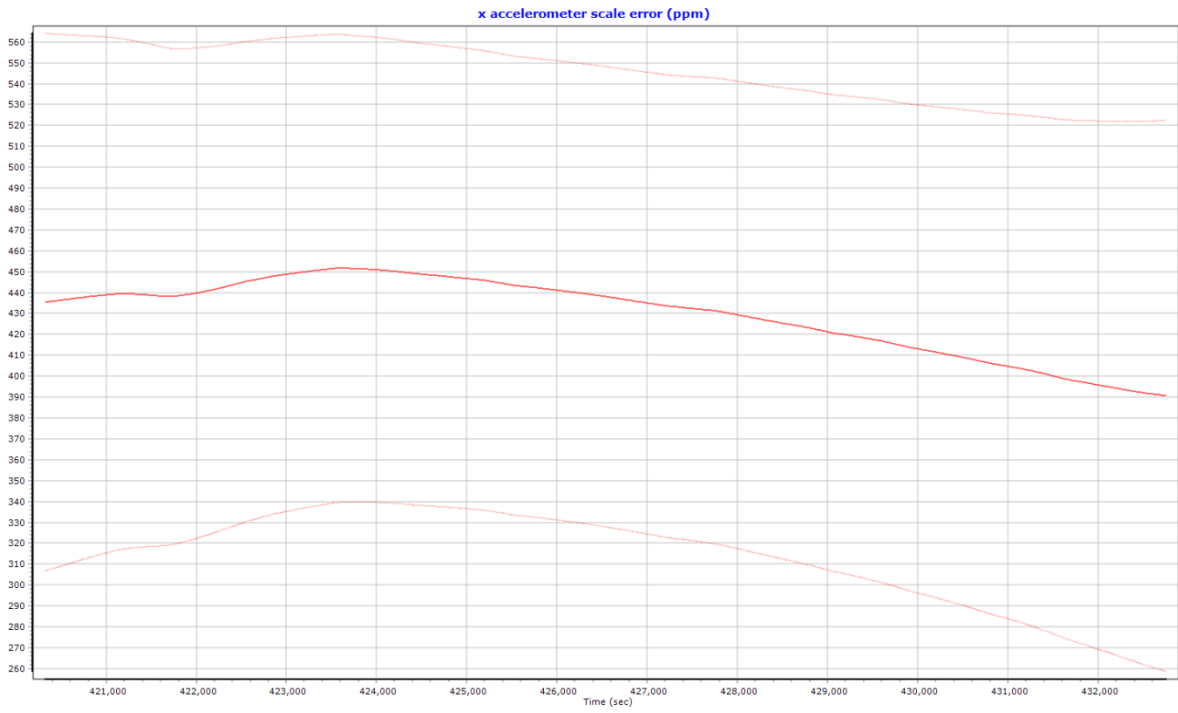
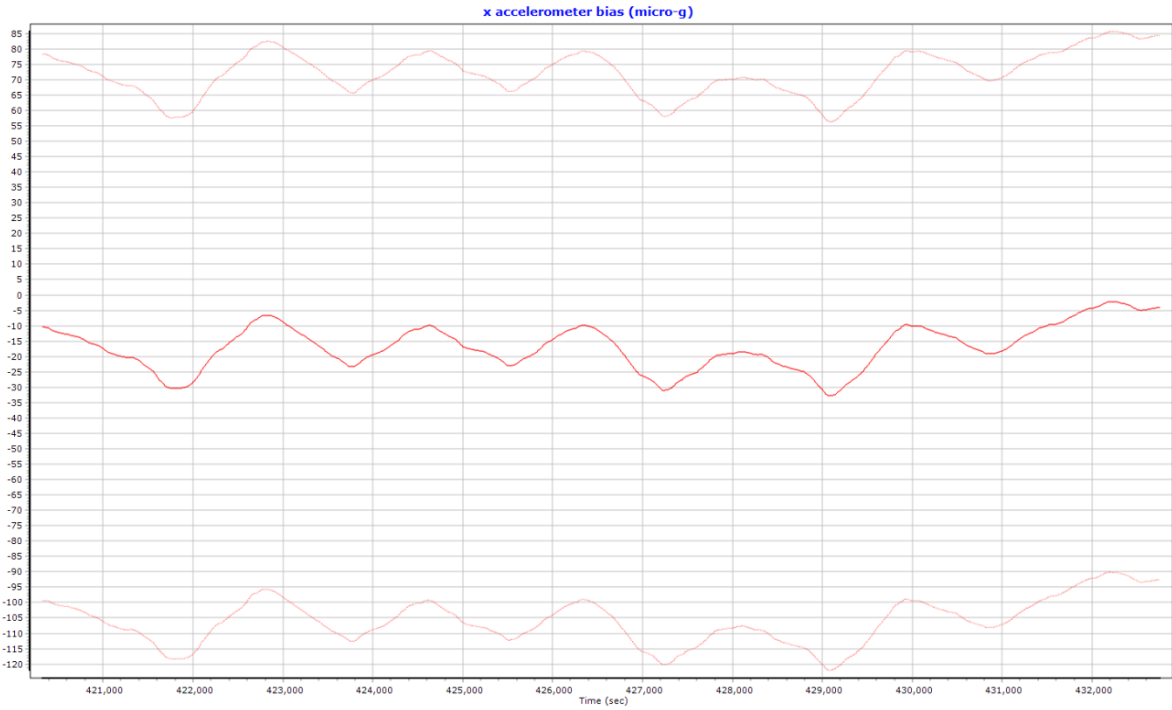
Start: 420322.602
 End: 432764.494

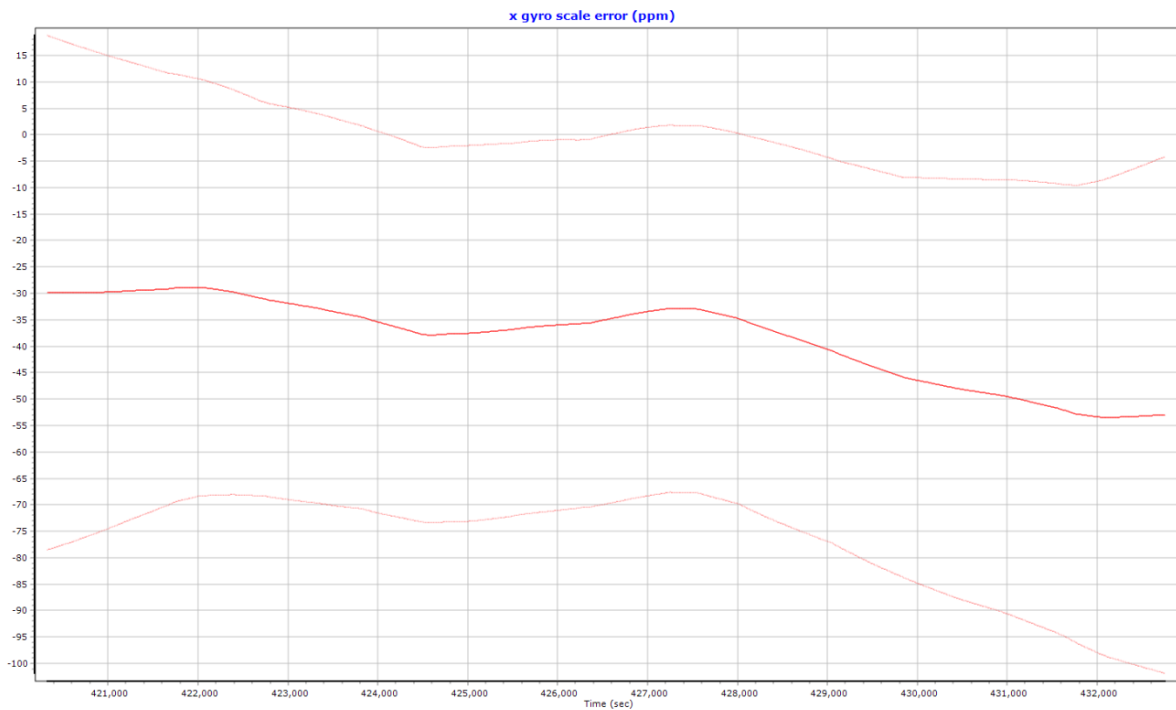
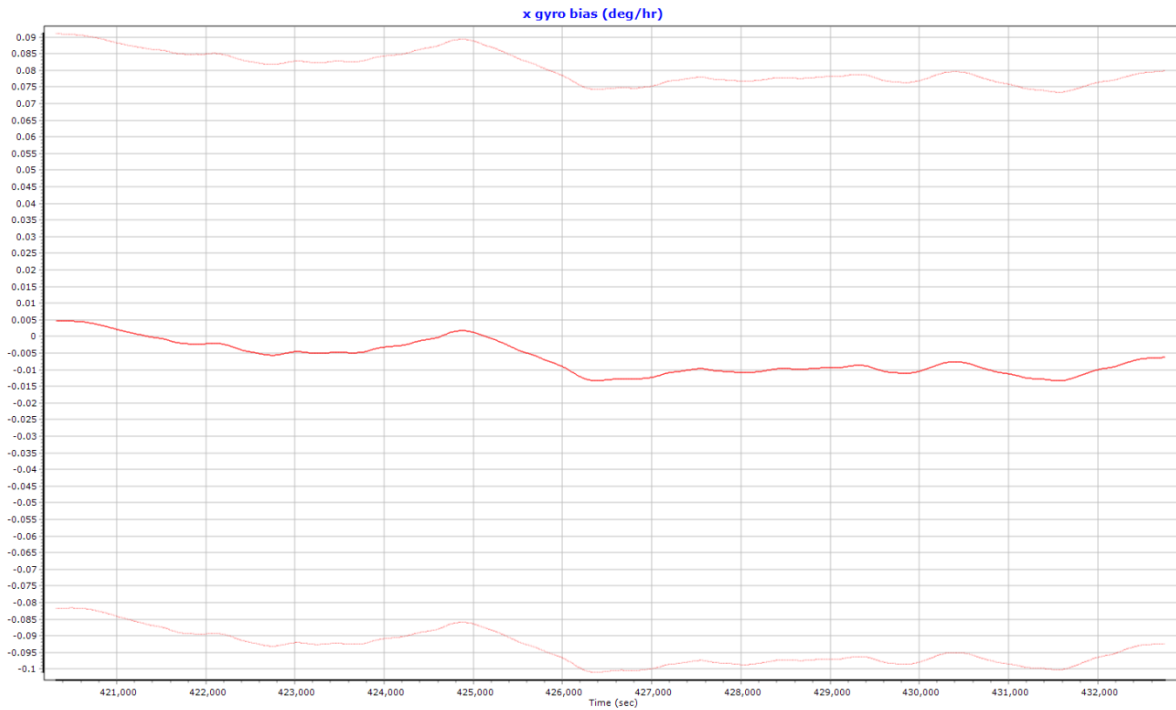
Entire time interval
 Seconds of start week

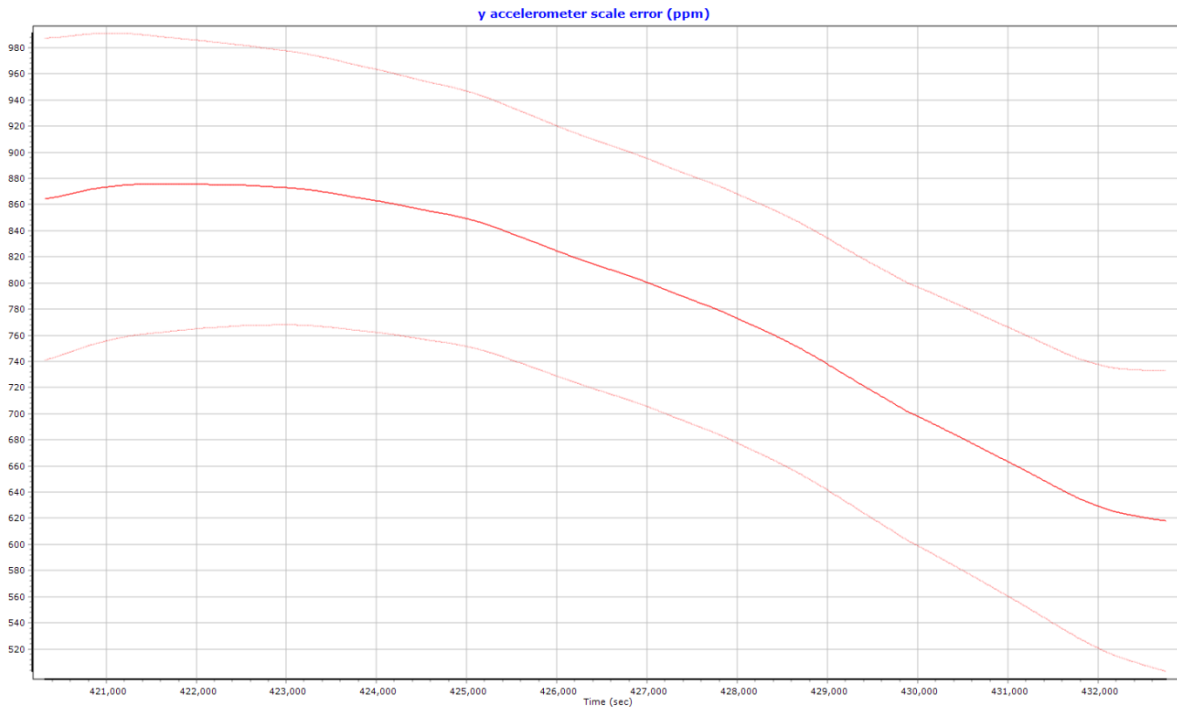
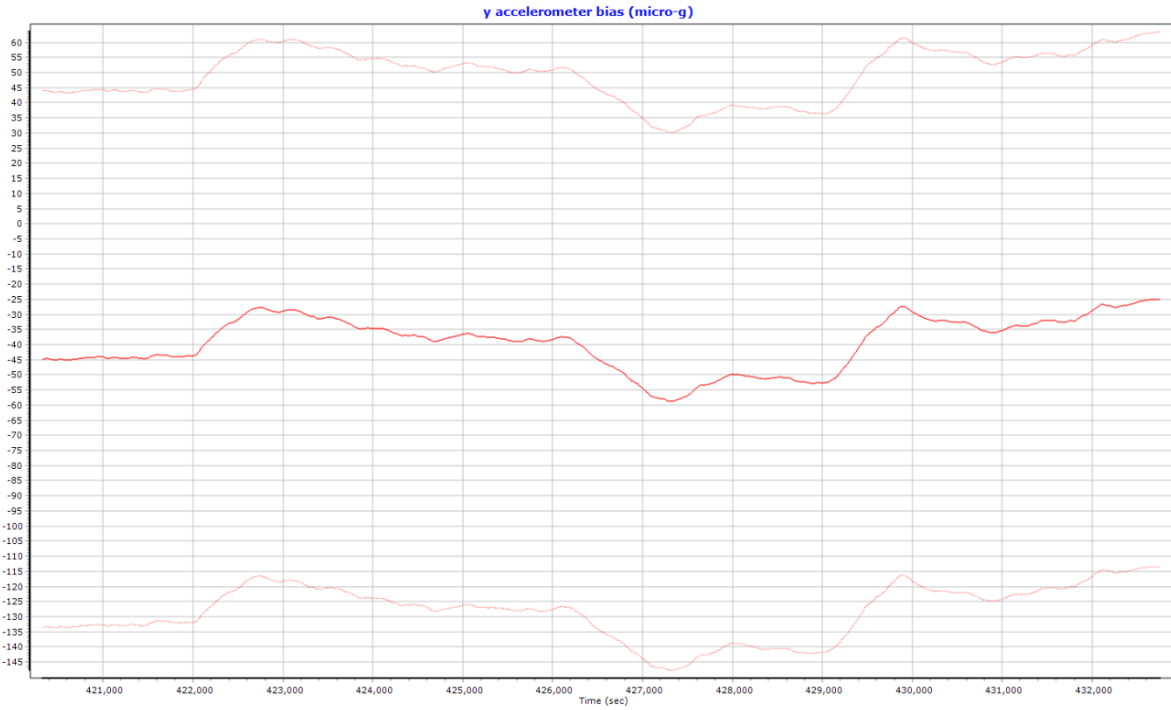
UTC Offset: 18.000

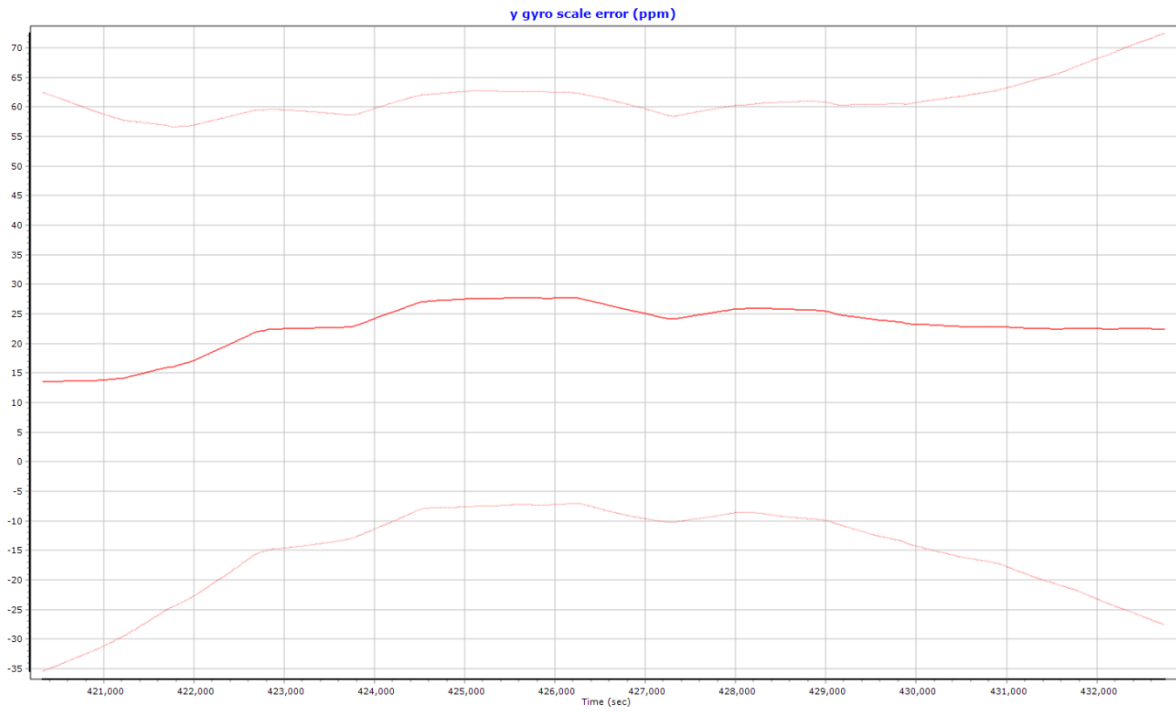
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

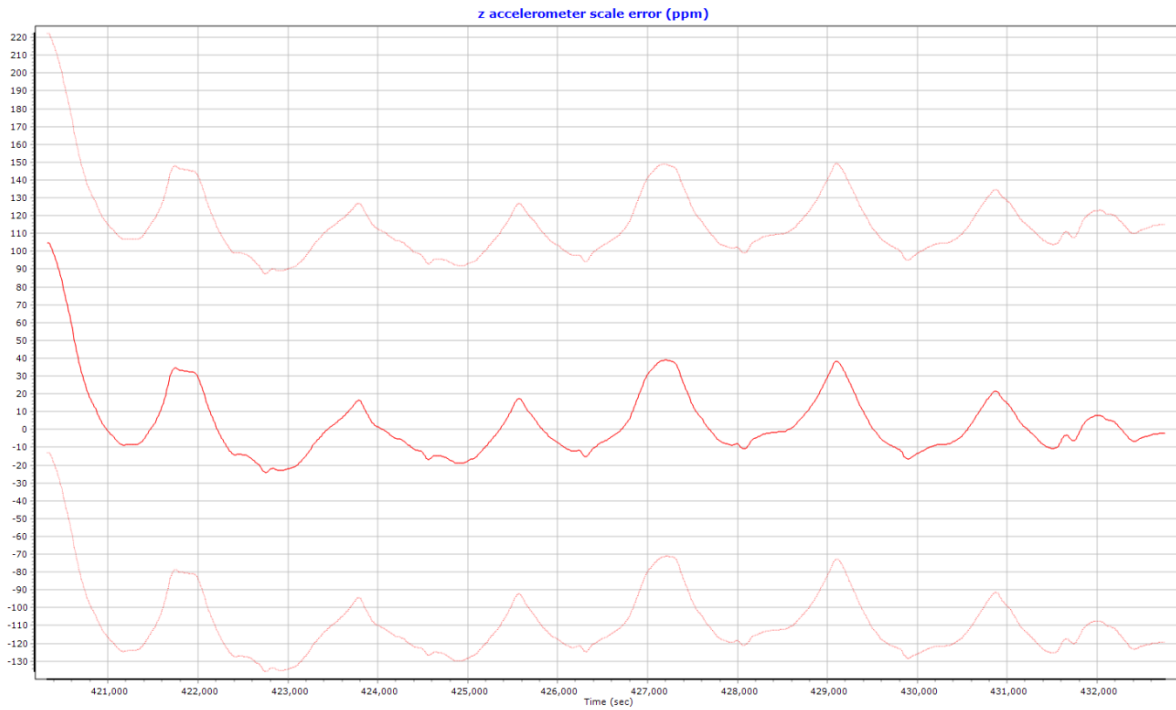
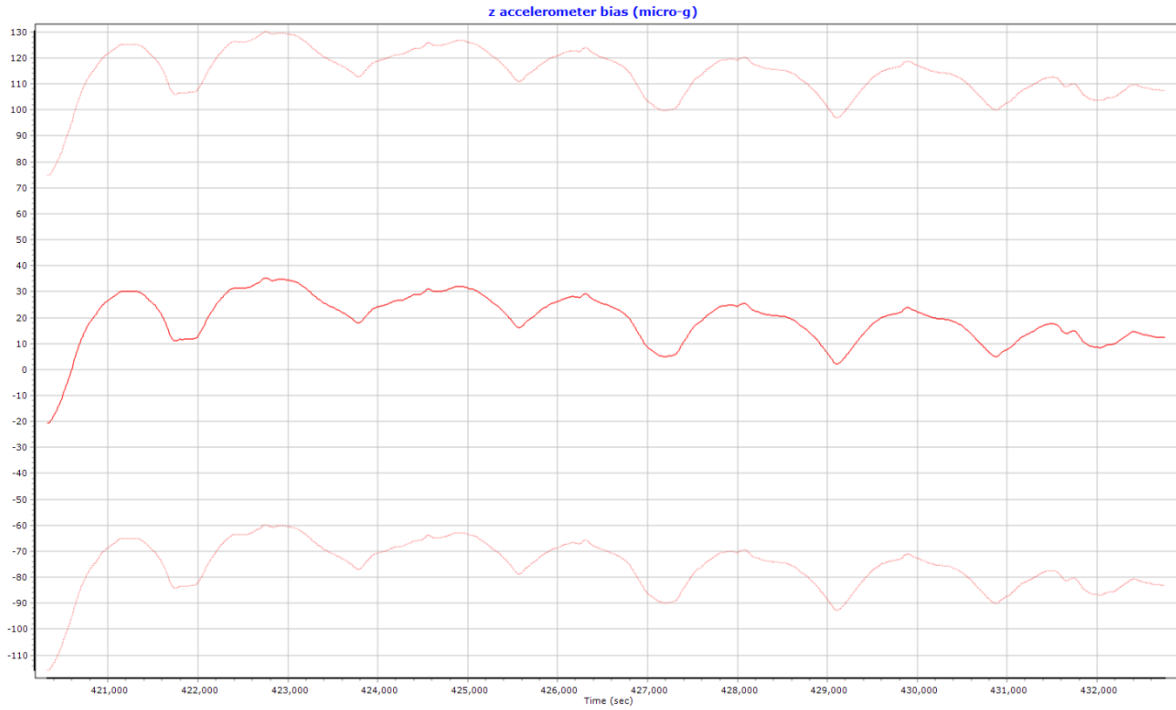
OK Cancel

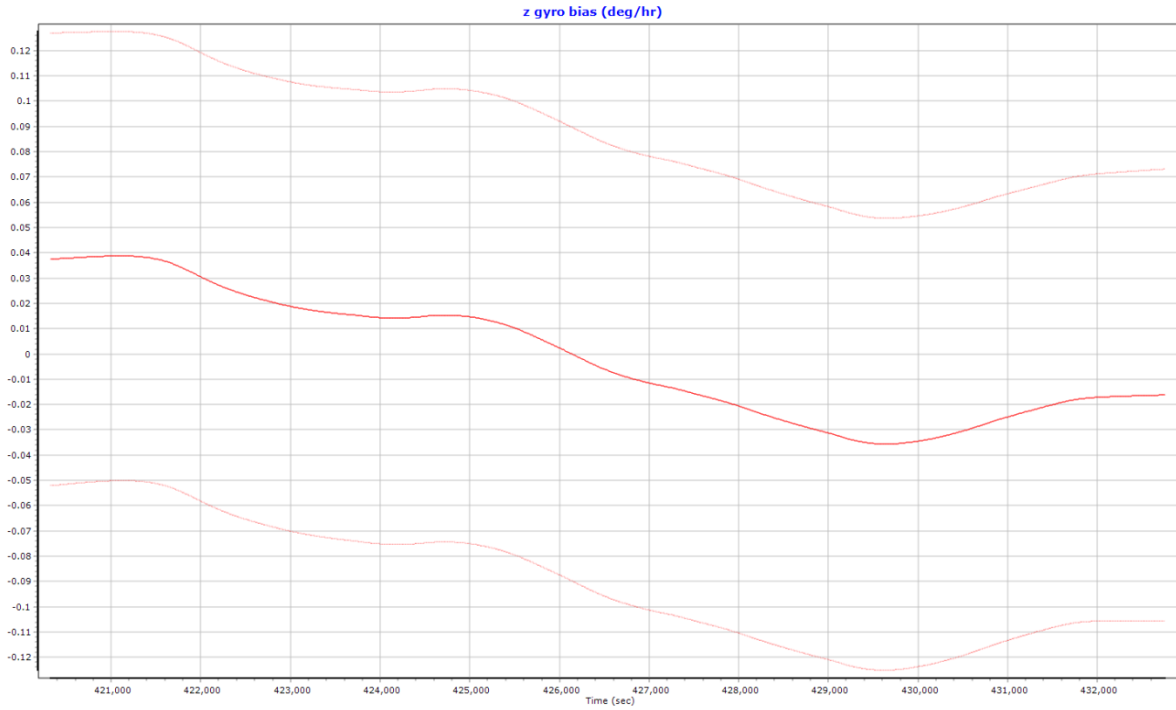




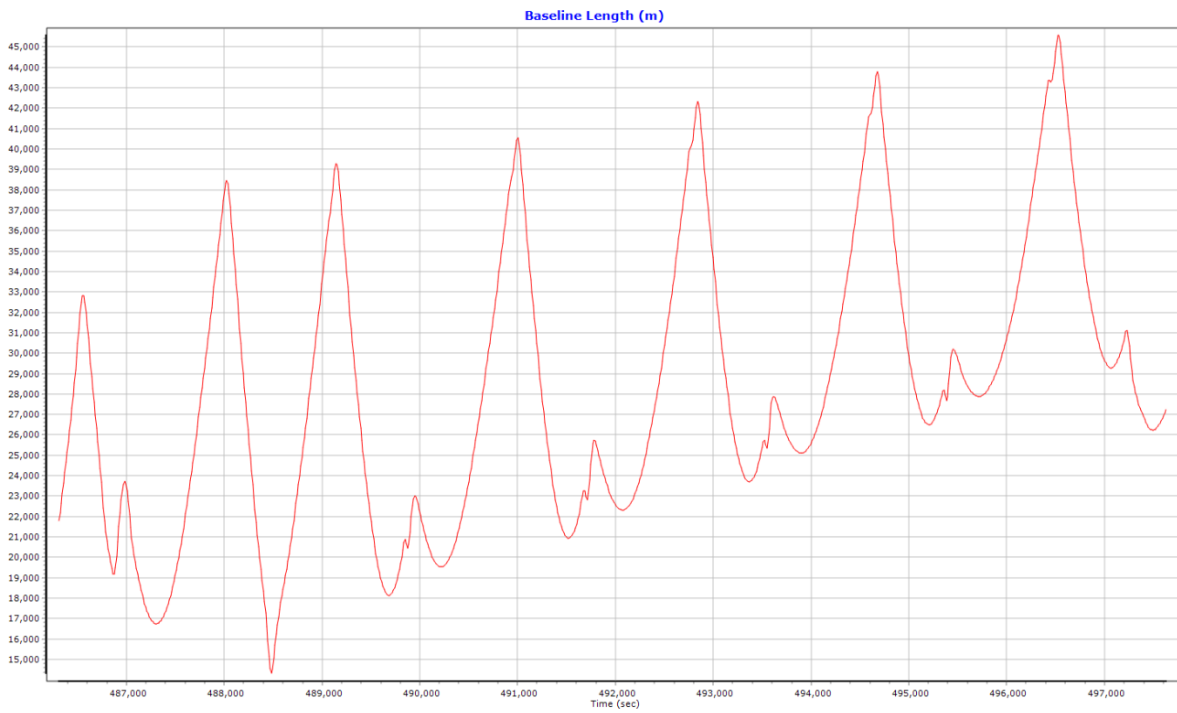
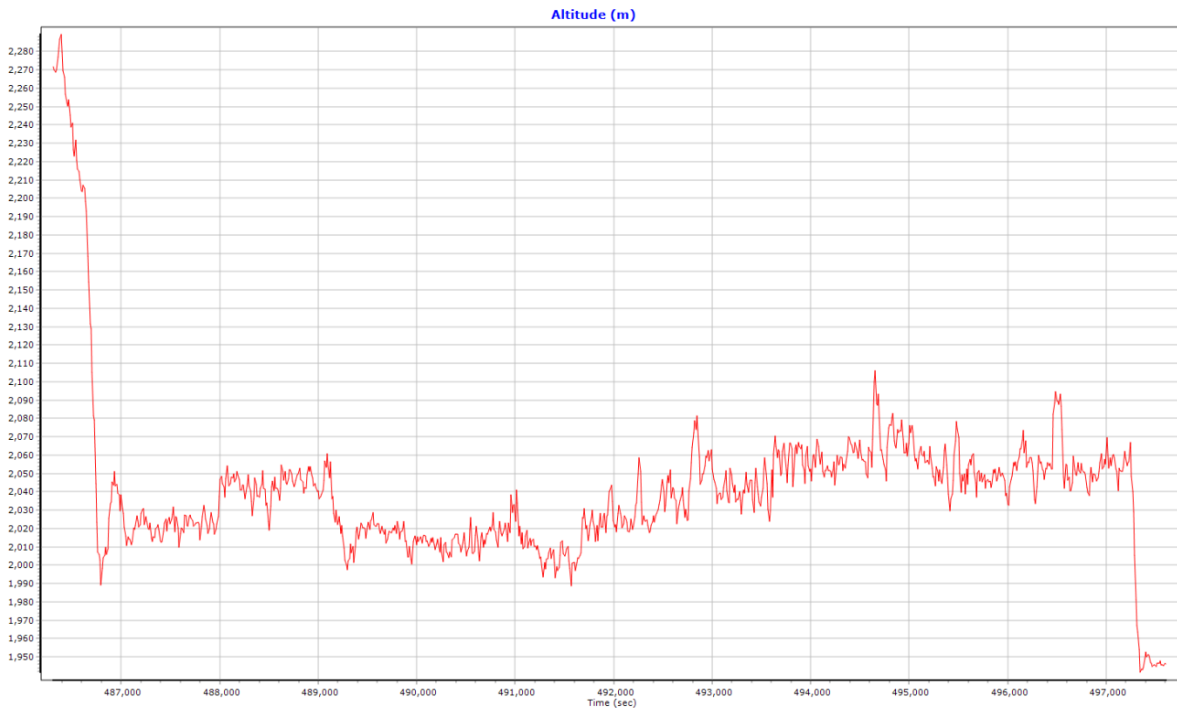


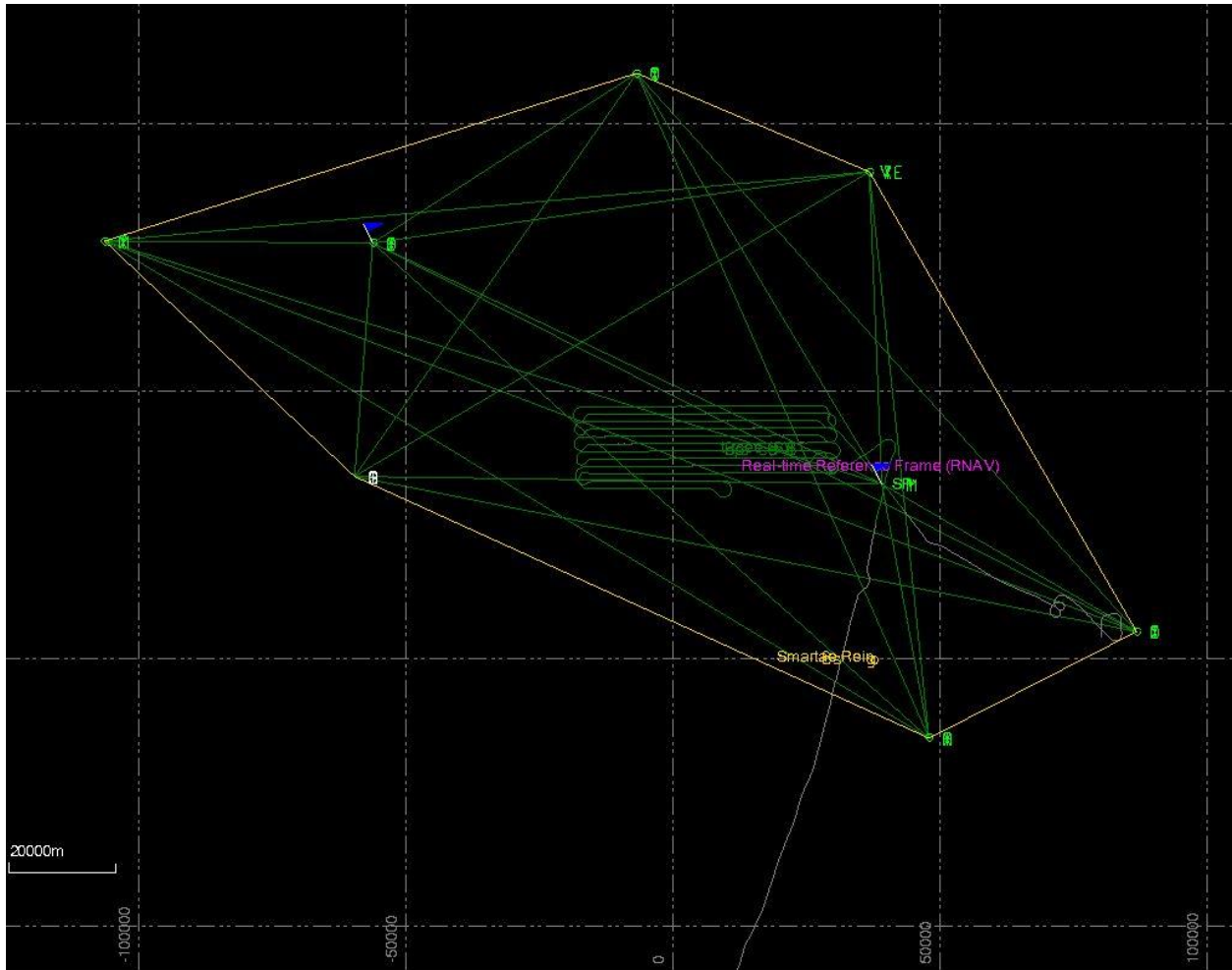






RBV18o68A







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

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: 10cm 50cm 1m 10m

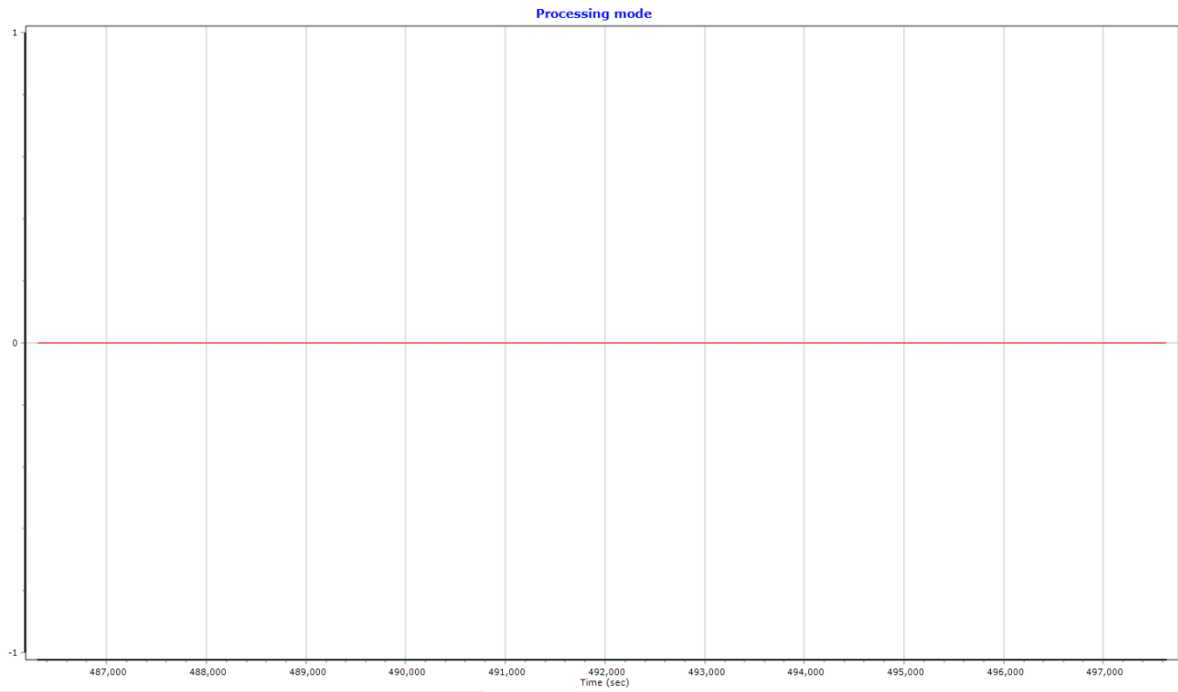
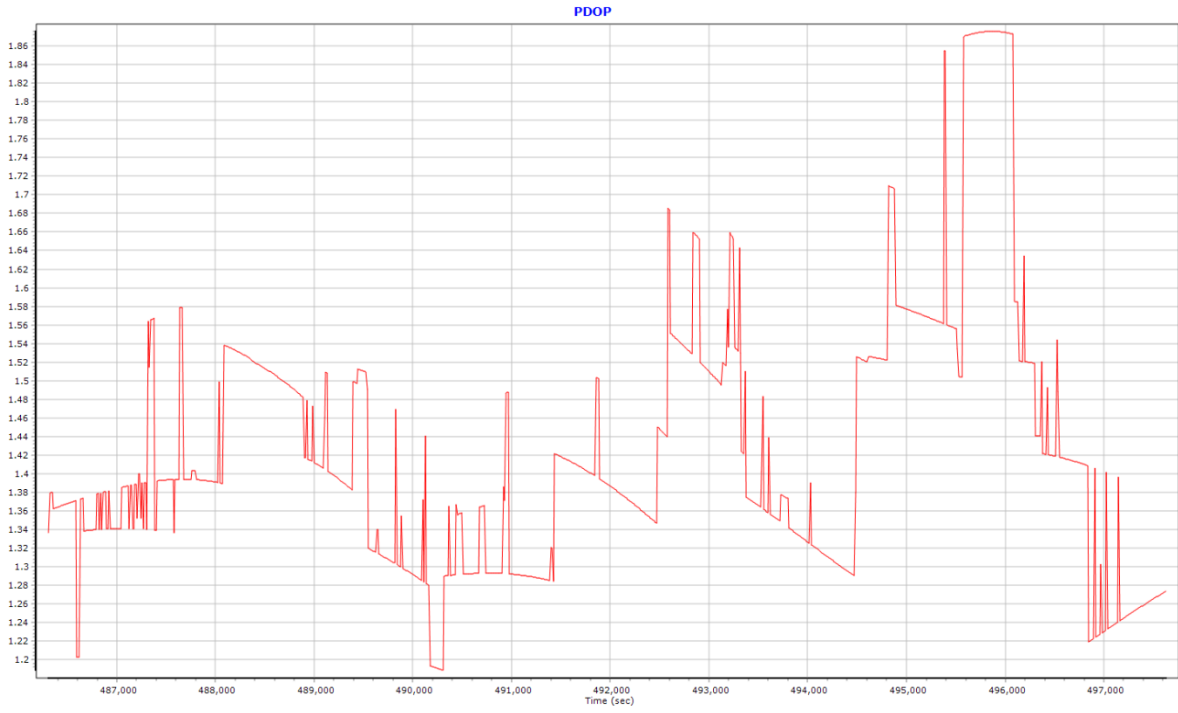
Aircraft to Stabilized Mount Mounting Angles

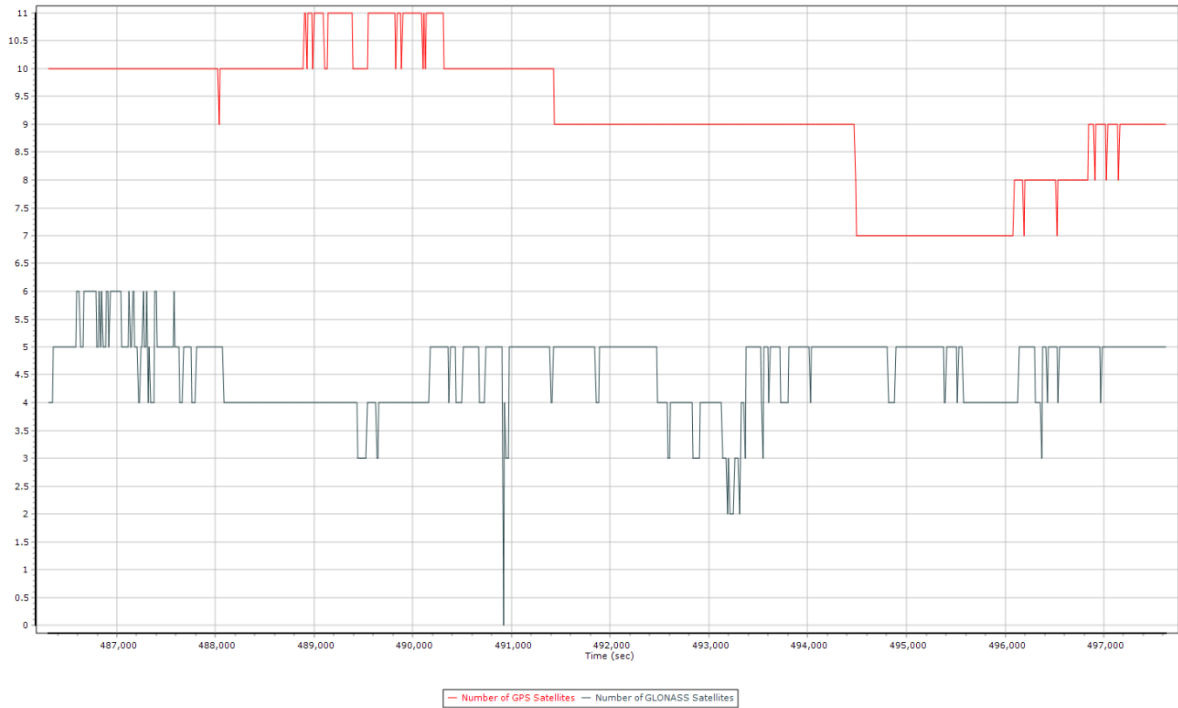
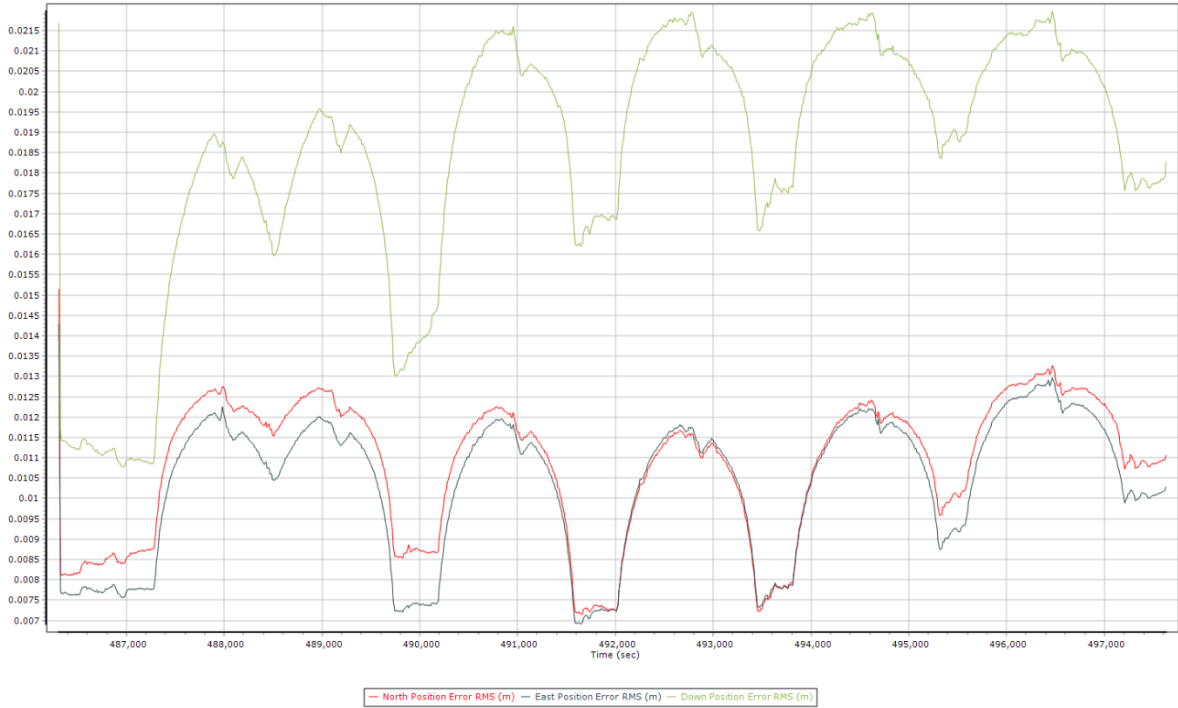
X:

Y:

Z:

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





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

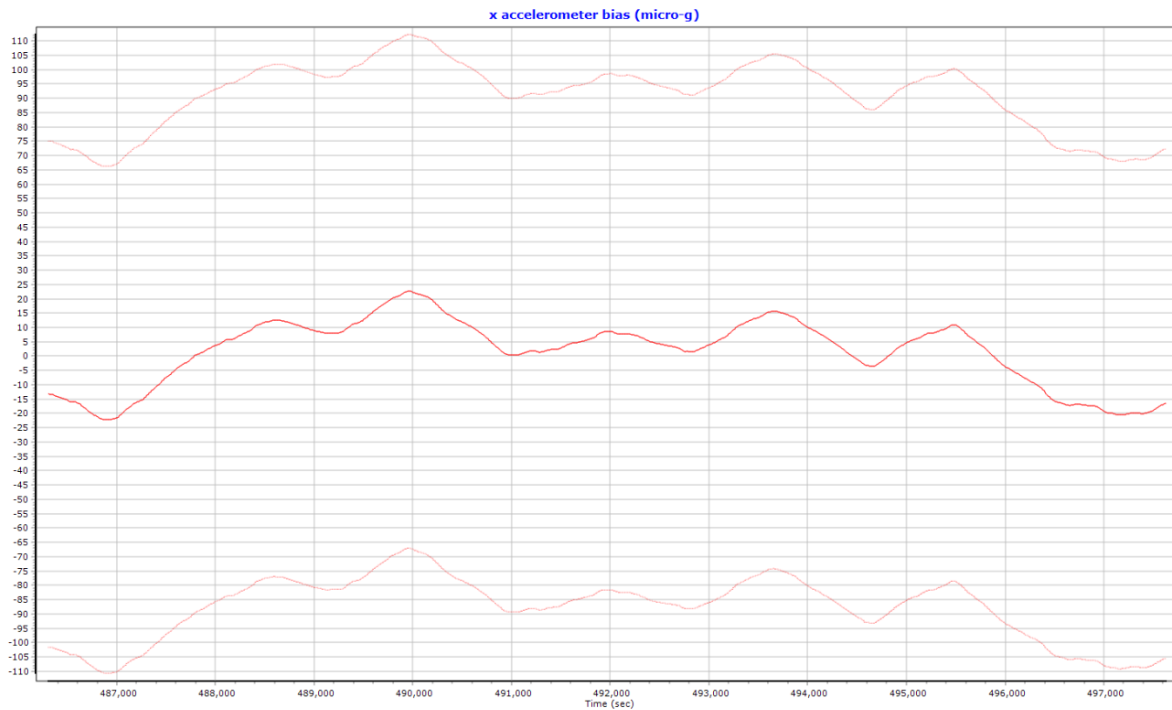
Start: 486307.920
End: 497644.547

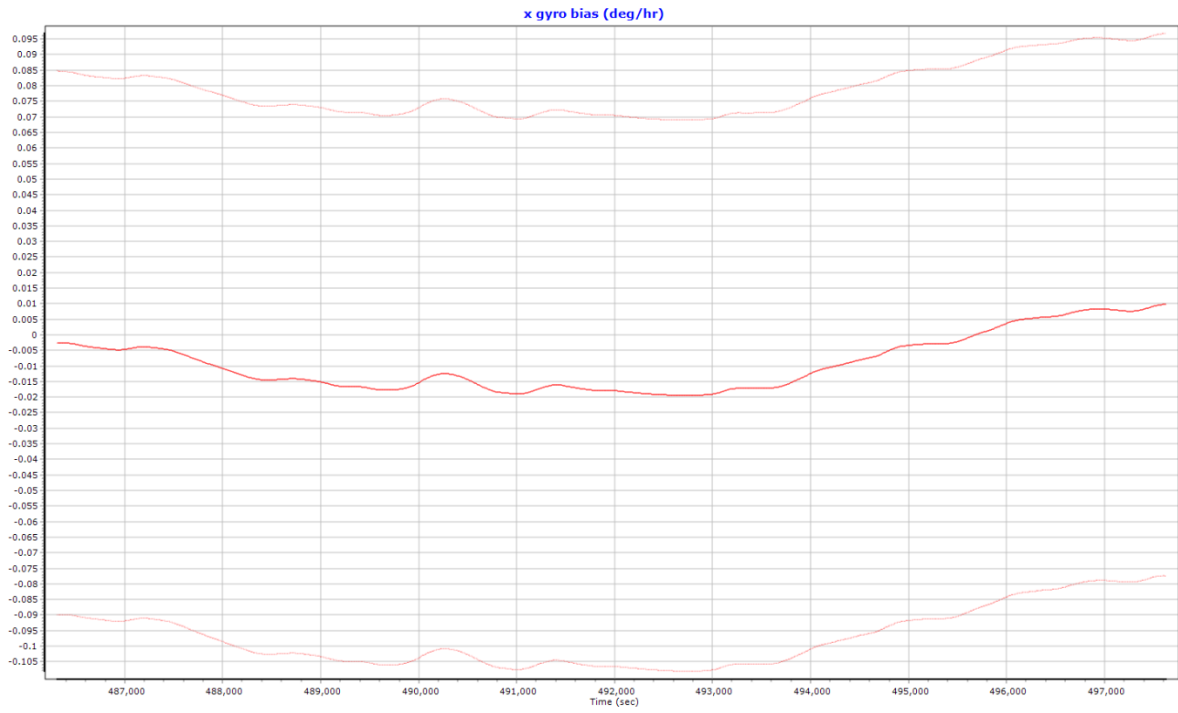
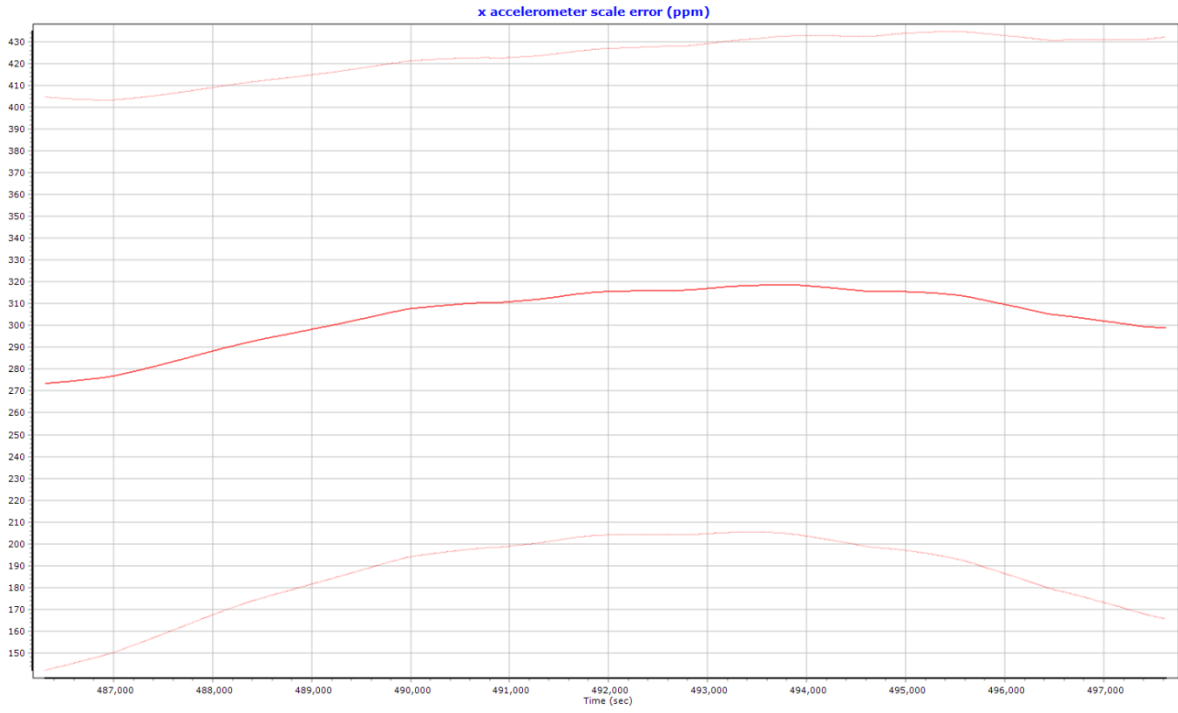
Entire time interval
 Seconds of start week

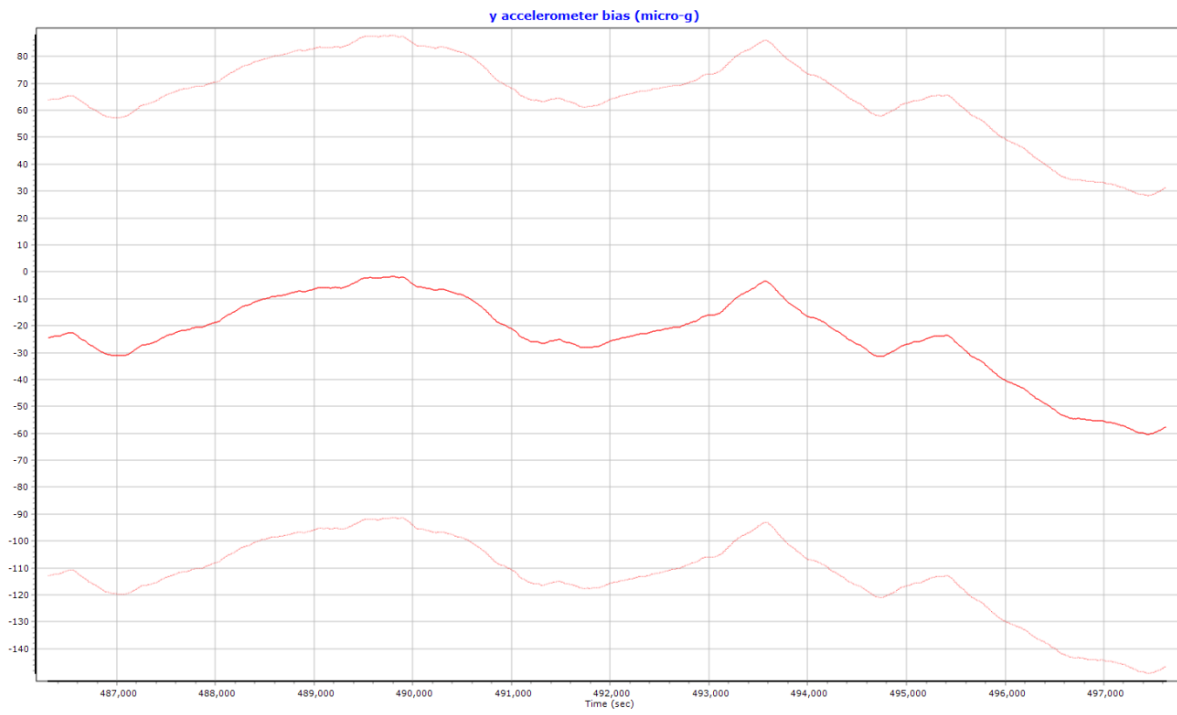
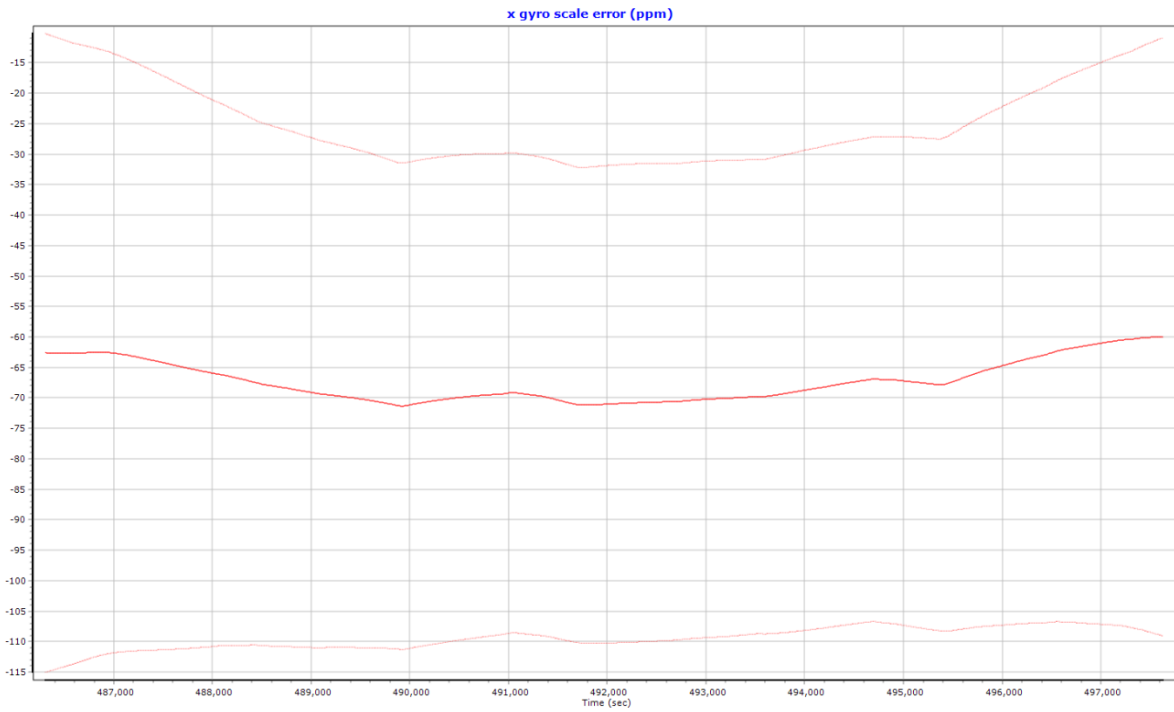
UTC Offset: 18.000

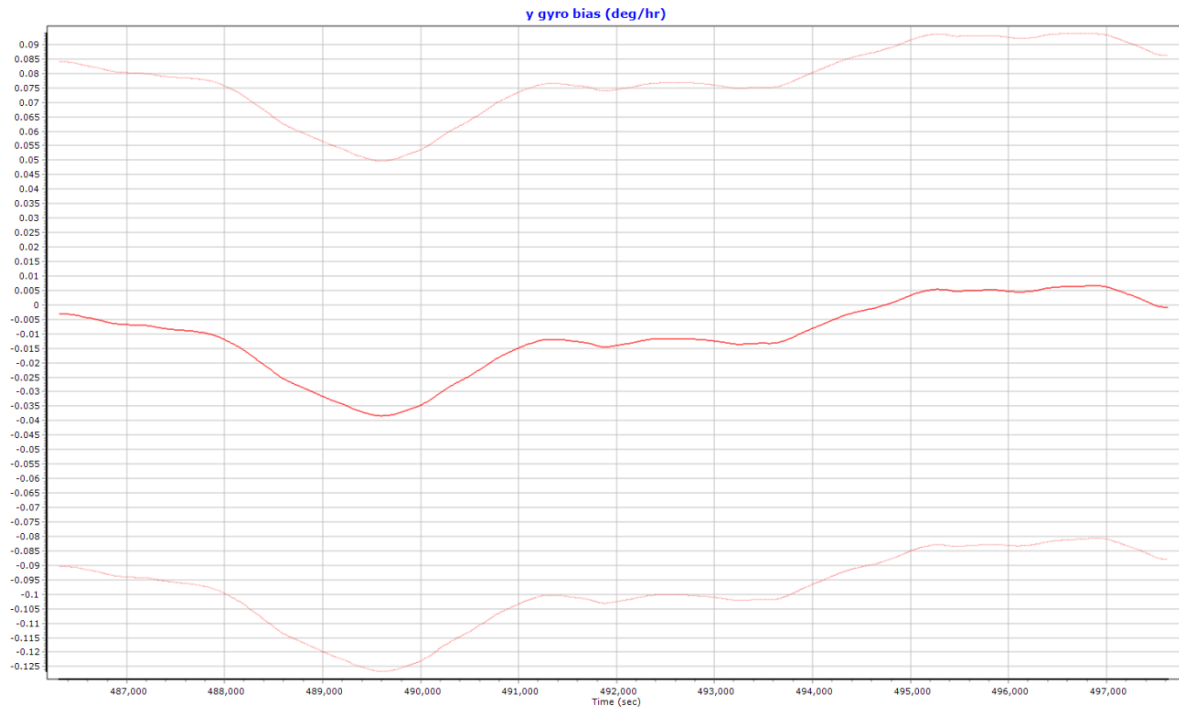
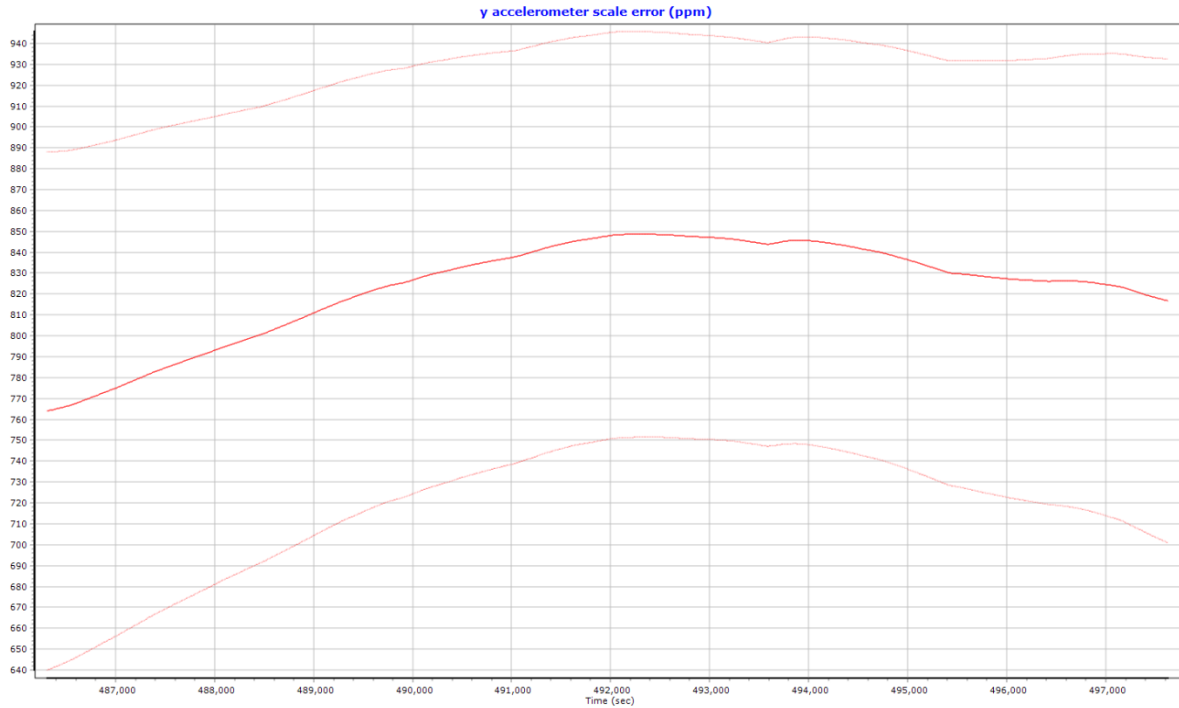
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

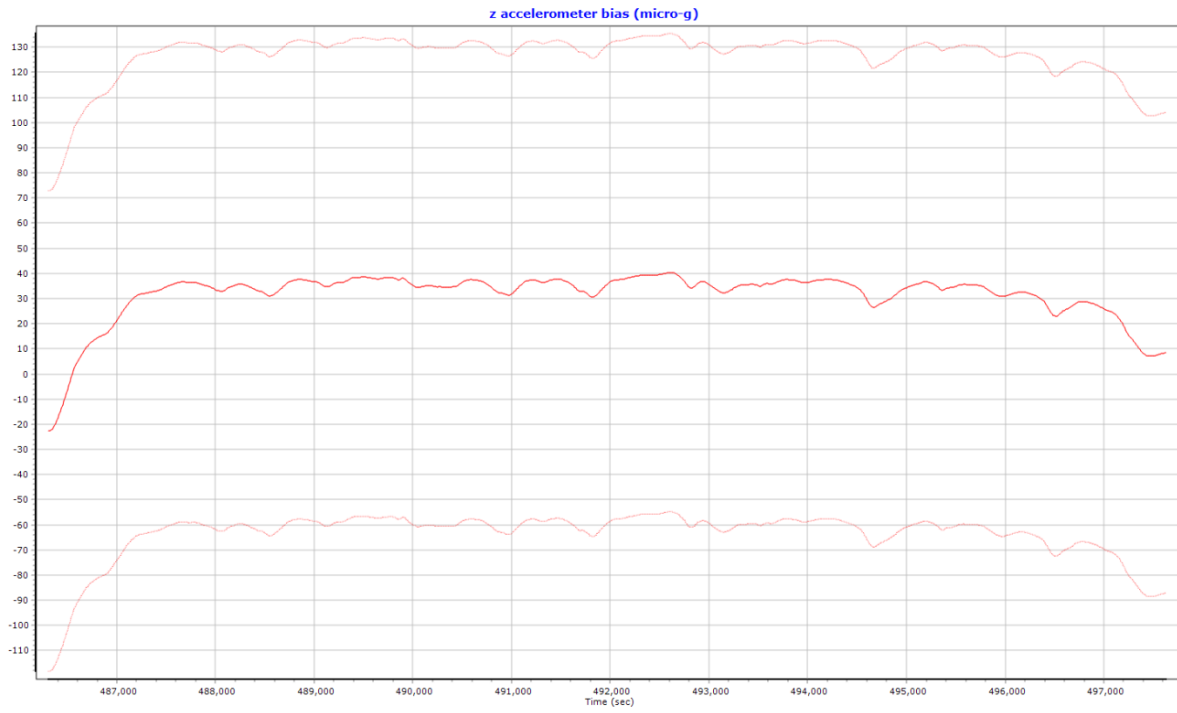
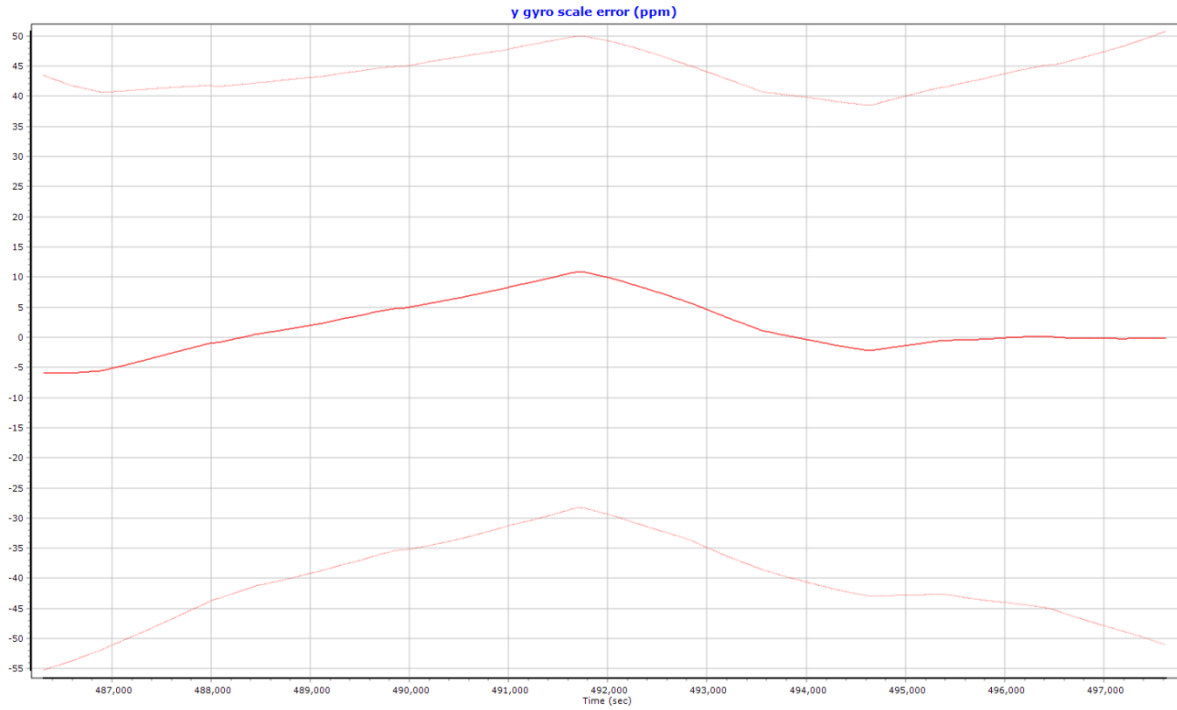
OK Cancel

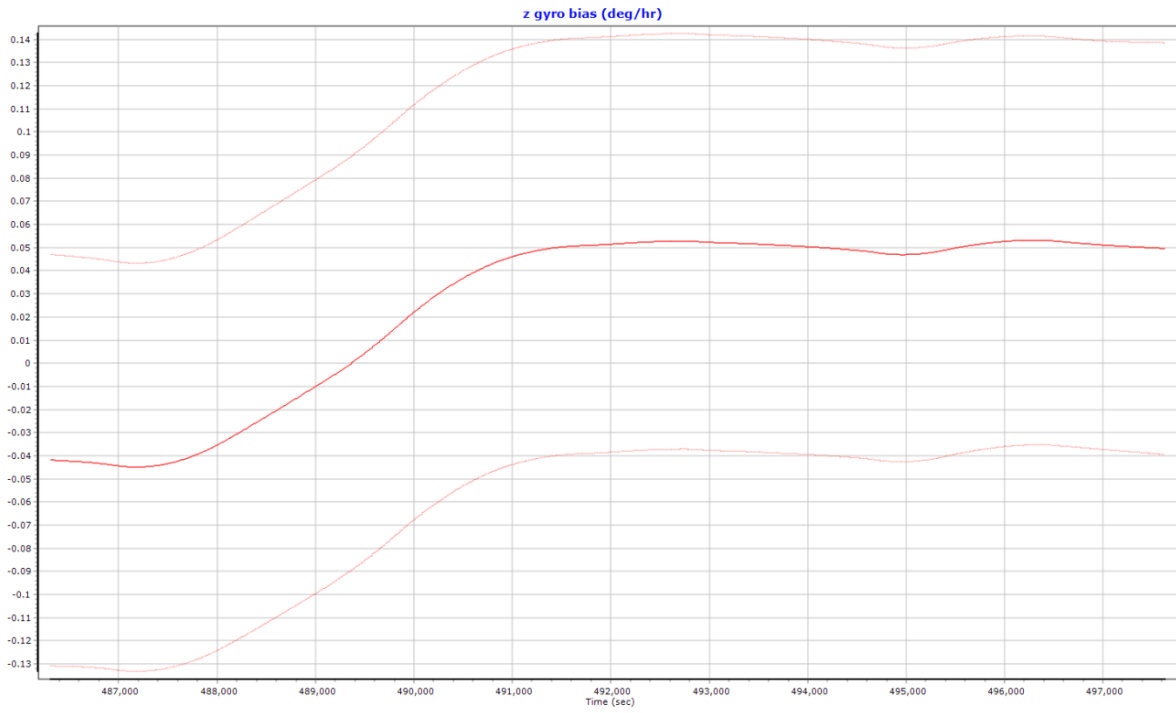
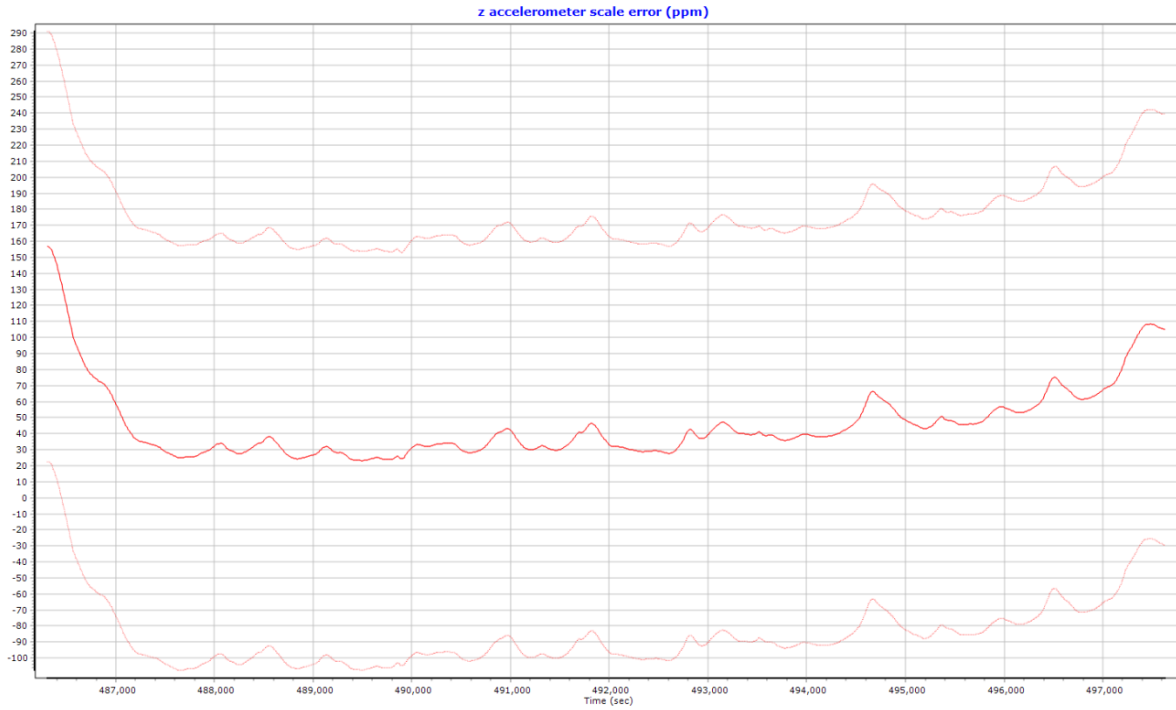


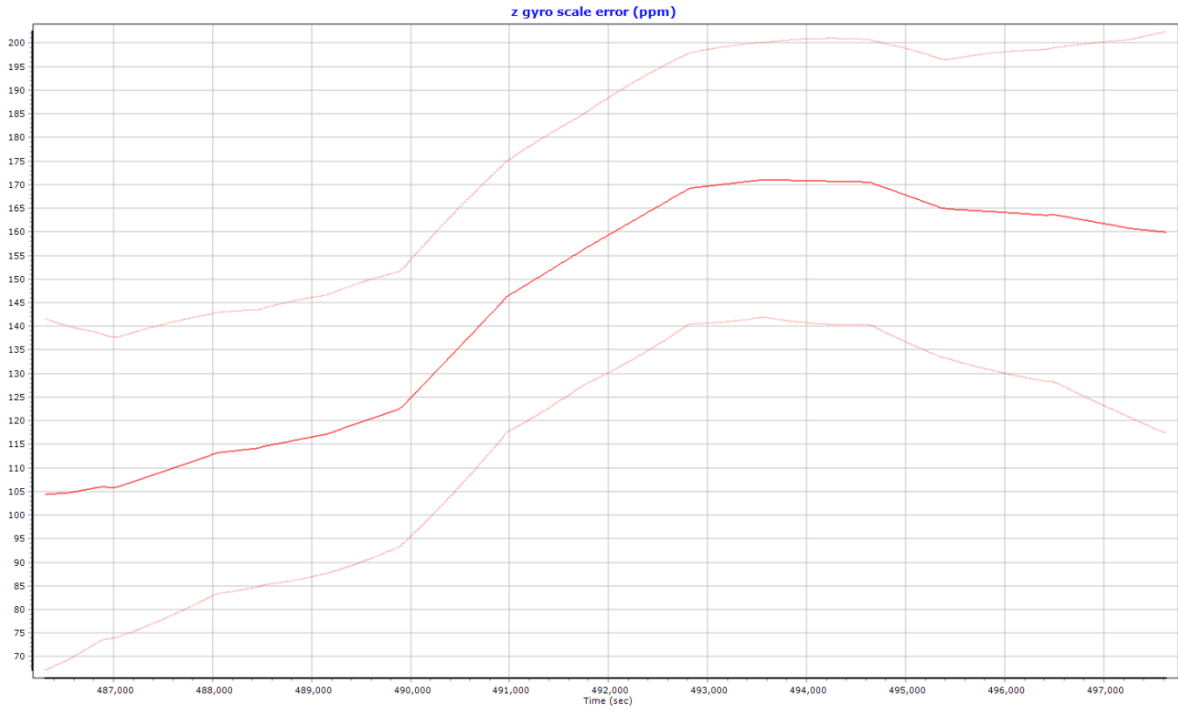




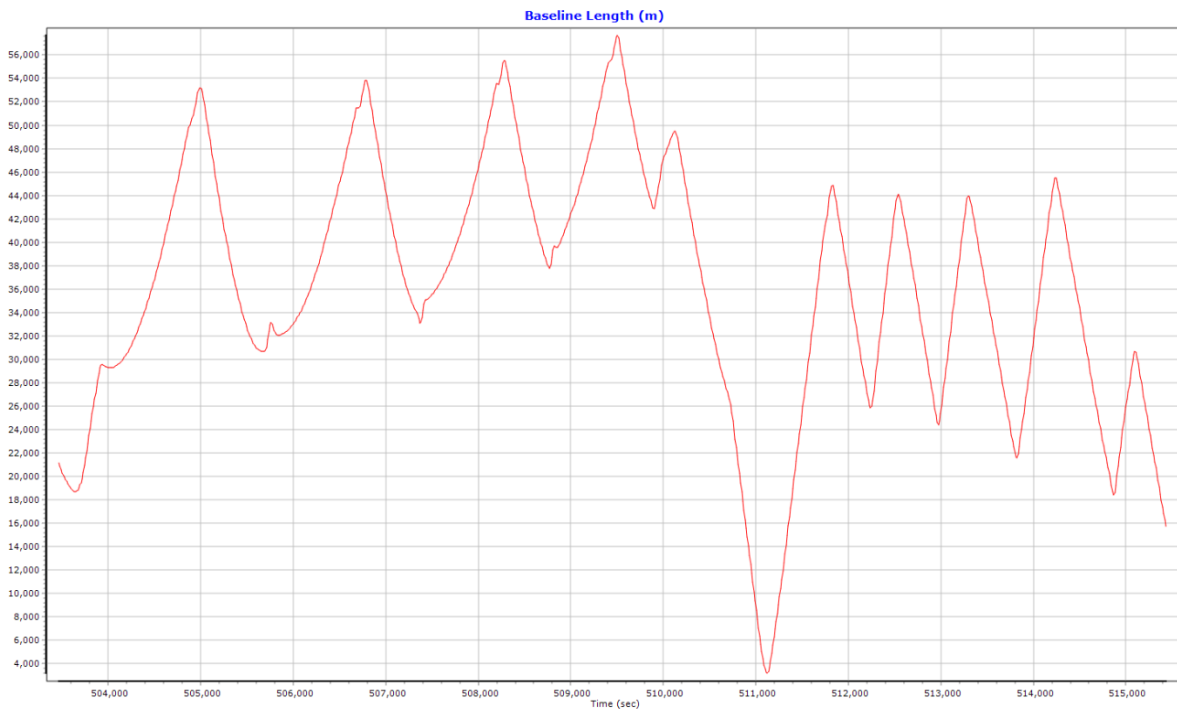
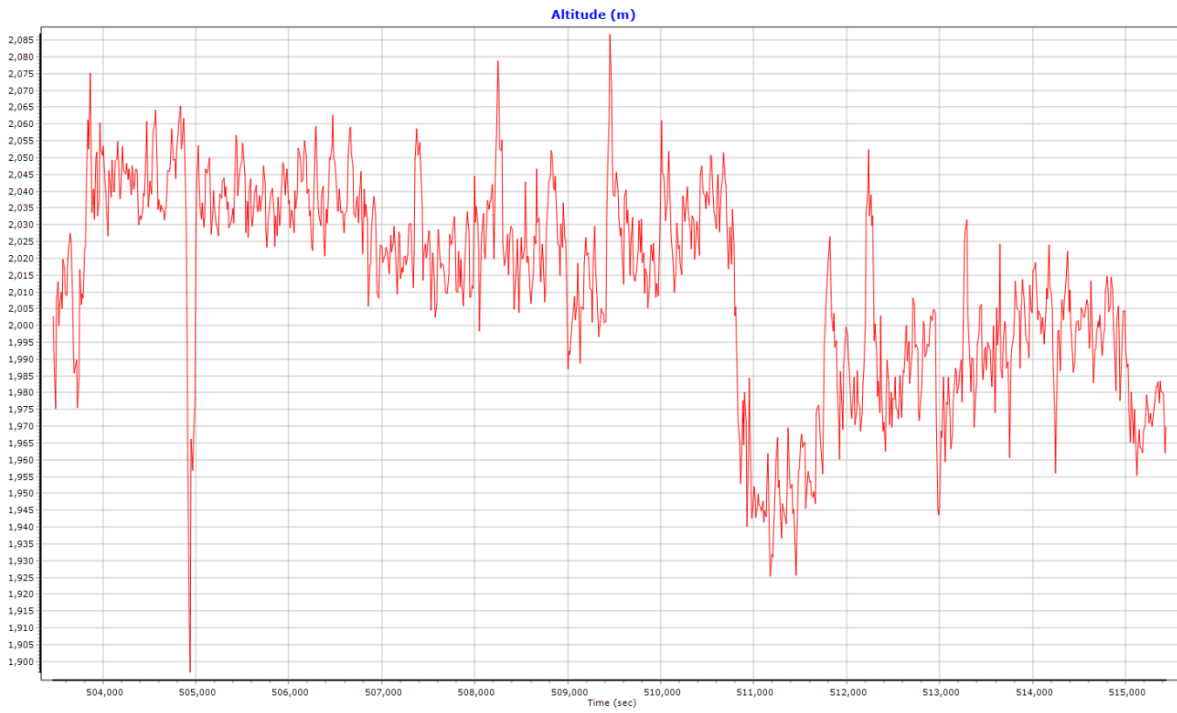


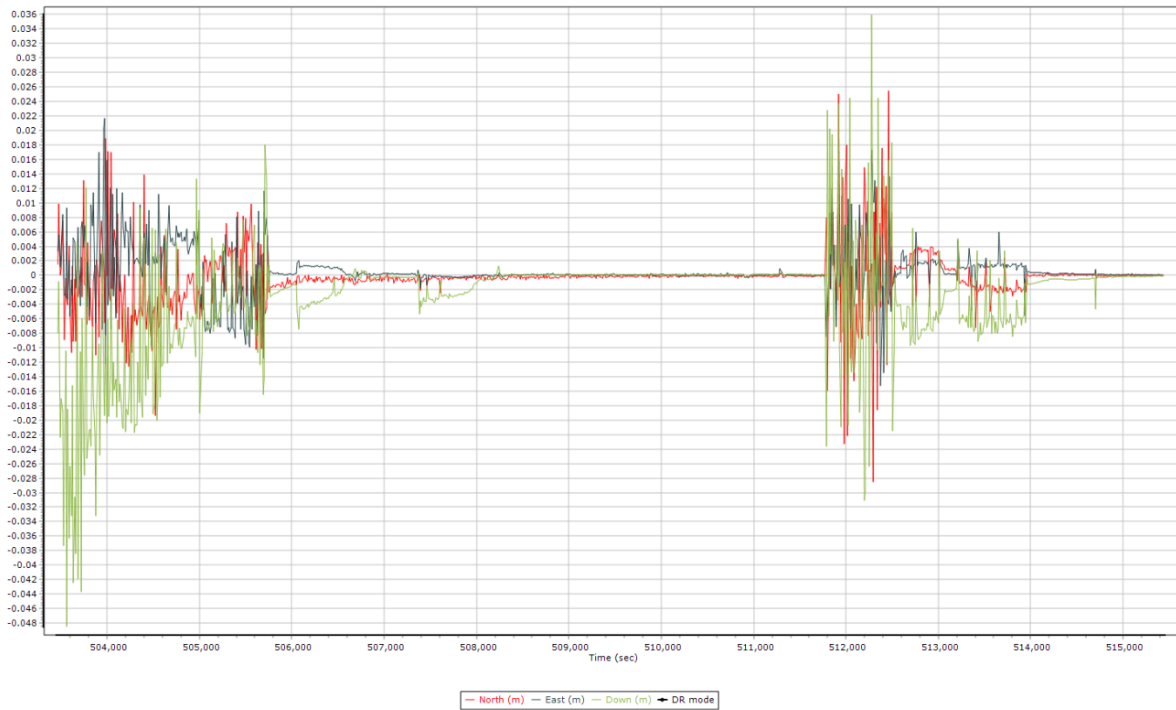
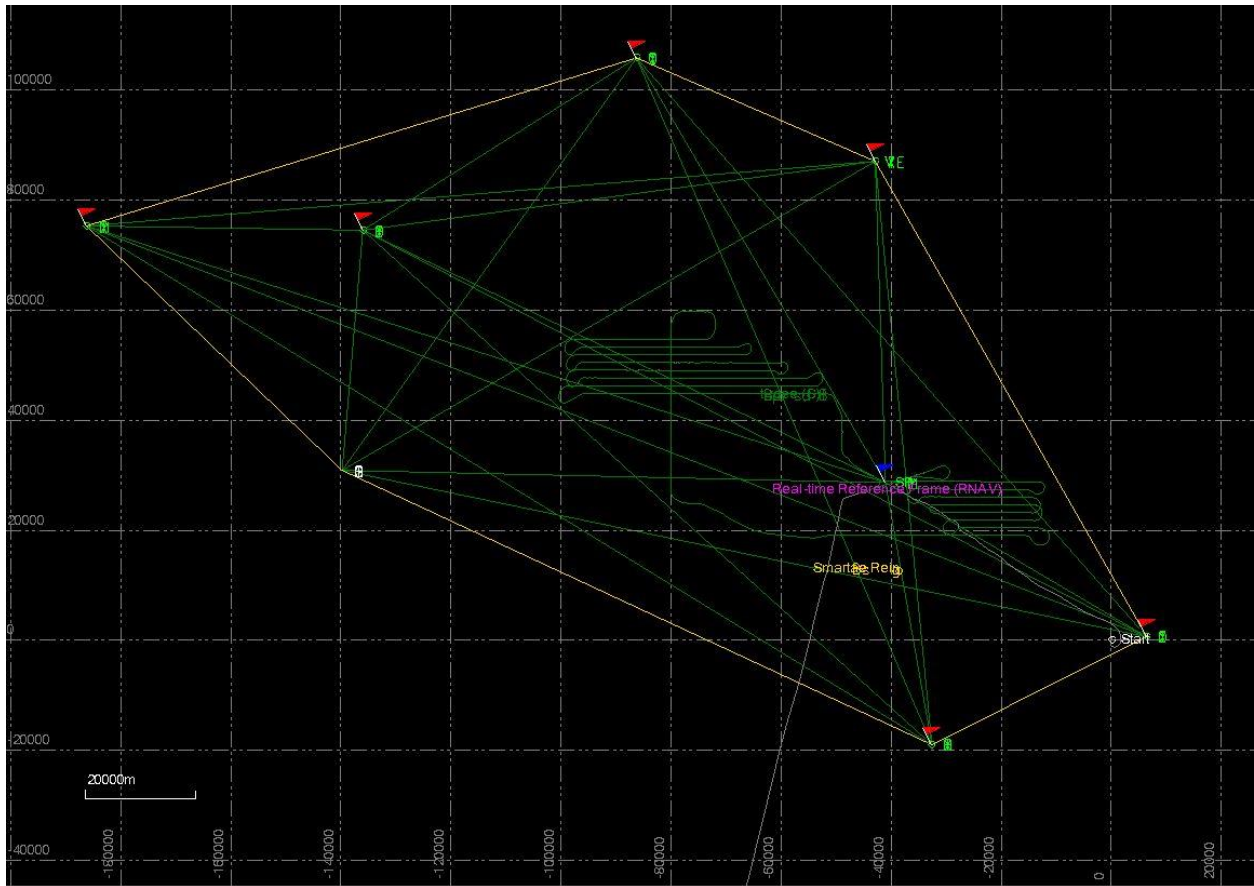






RBV18o68B





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	0.000 m
Y	0.000 m
Z	0.000 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	-0.031 m
Y	0.004 m
Z	-0.611 m

Aircraft to Stabilized Mount Mounting Angles

X	0.000 deg
Y	0.000 deg
Z	0.000 deg

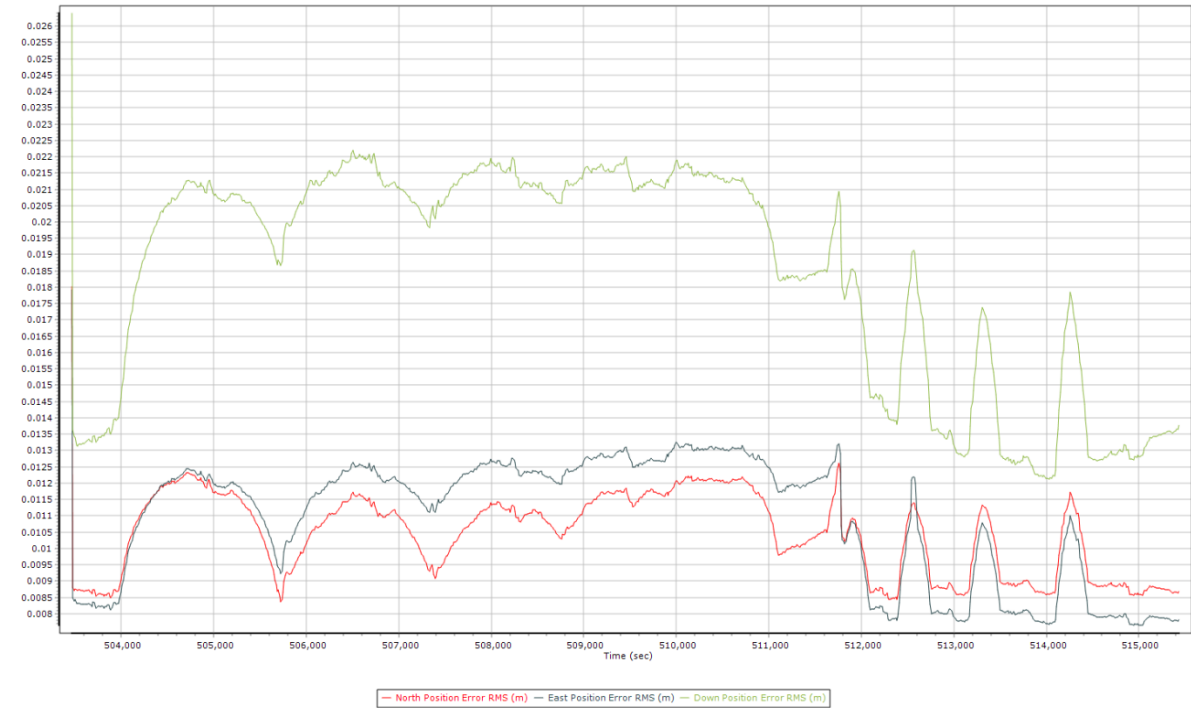
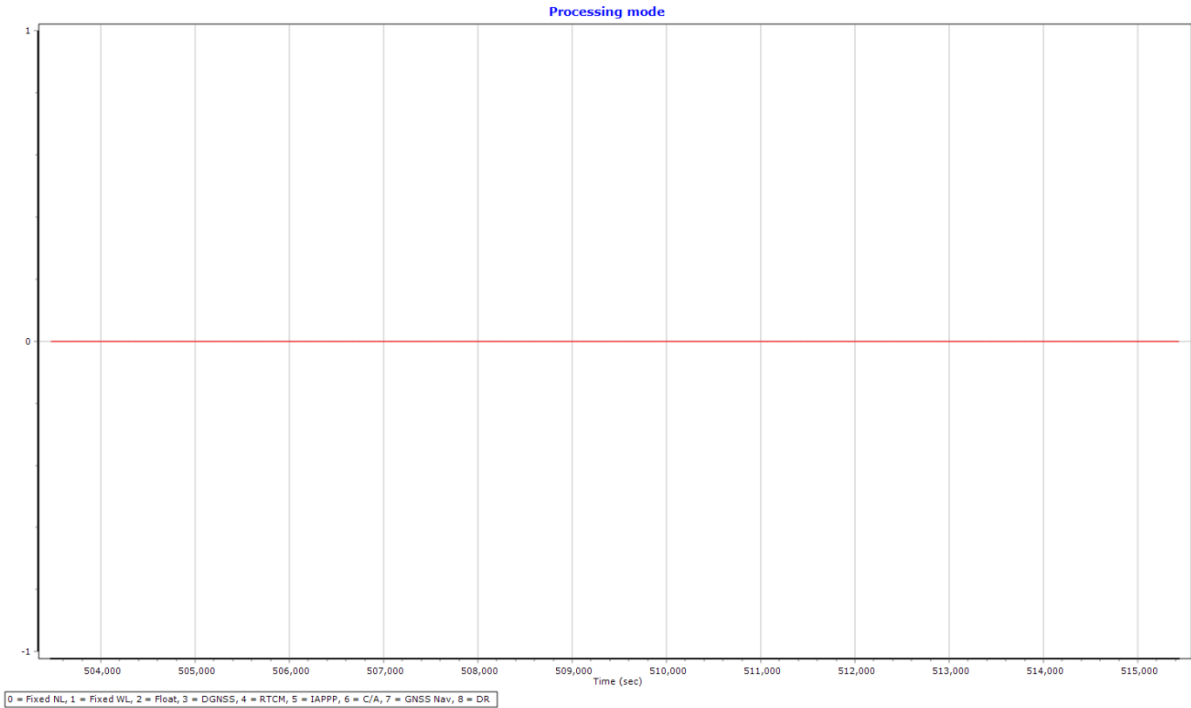
Standard Deviation

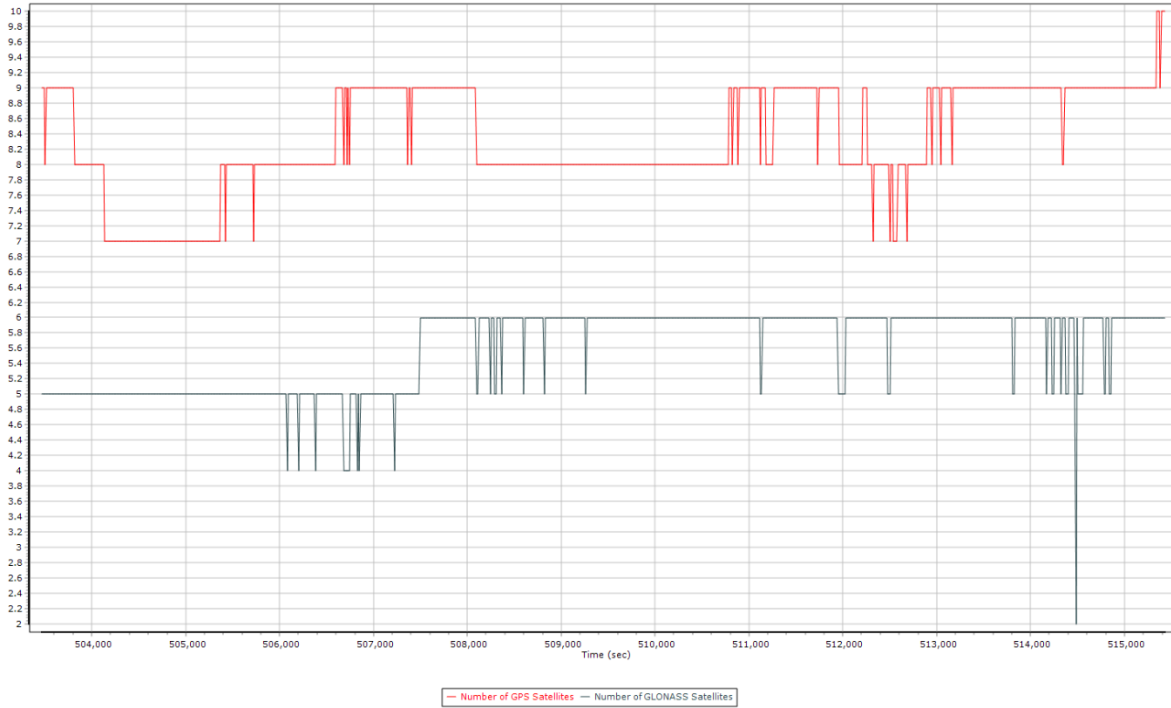
<3cm 10cm 50cm 1m 10m

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

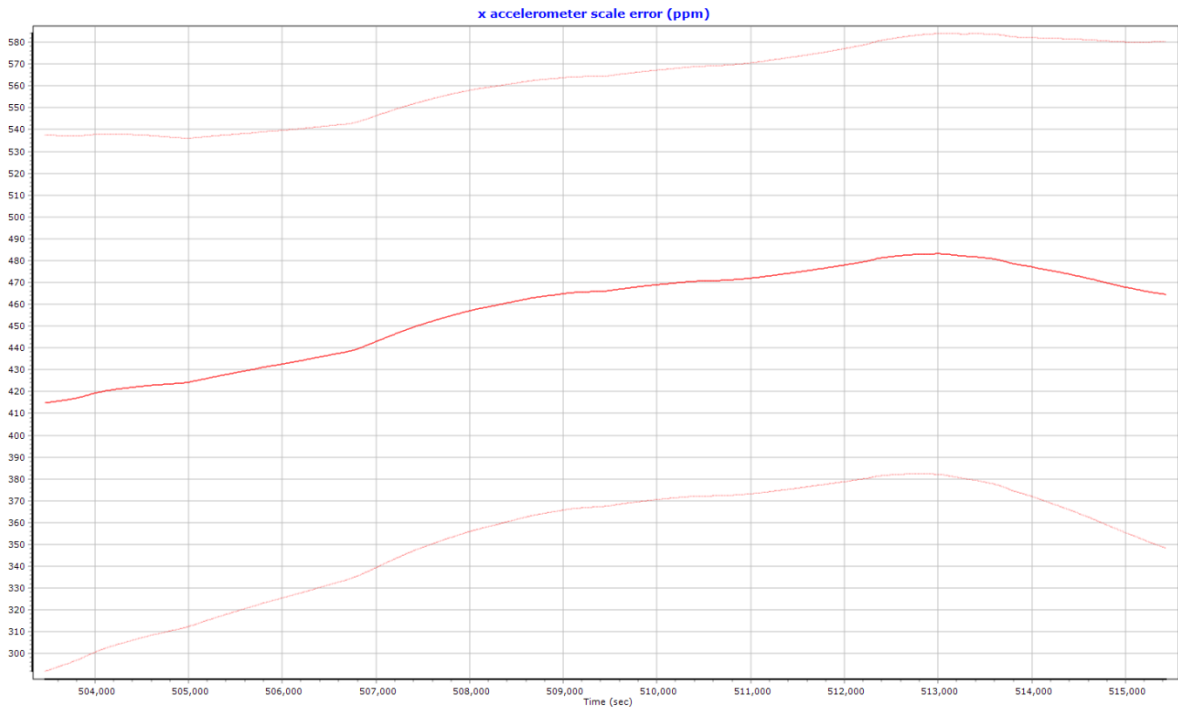
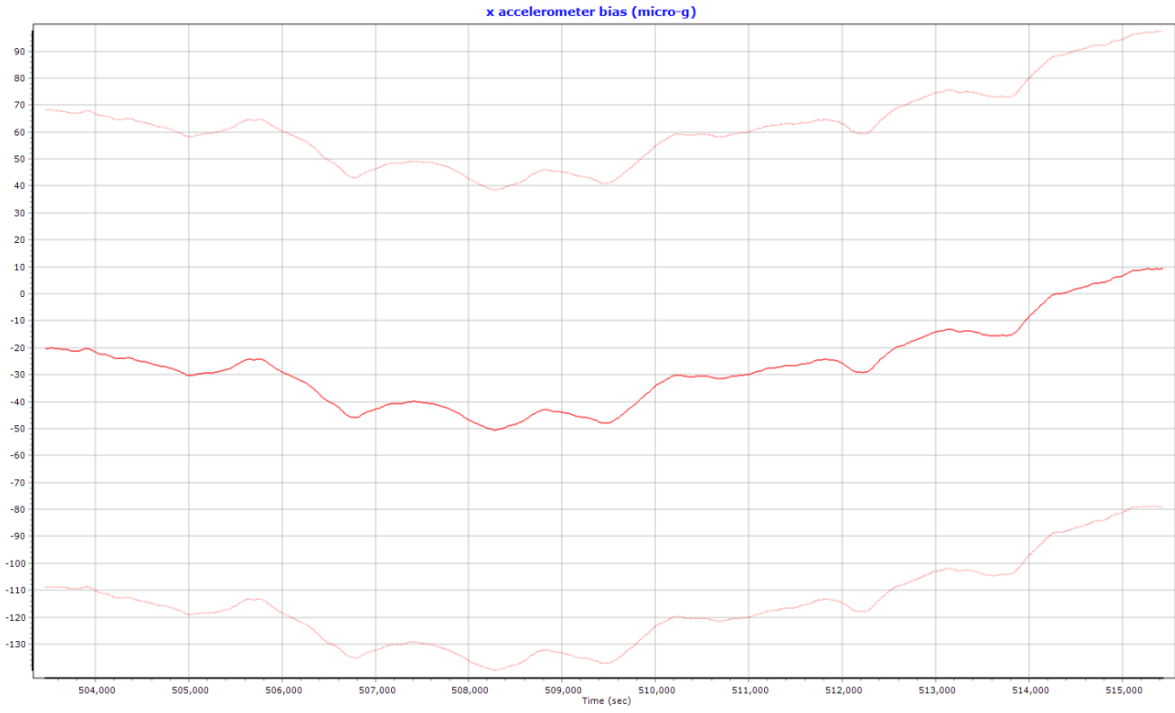
Start: 503465.152
 End: 515453.966

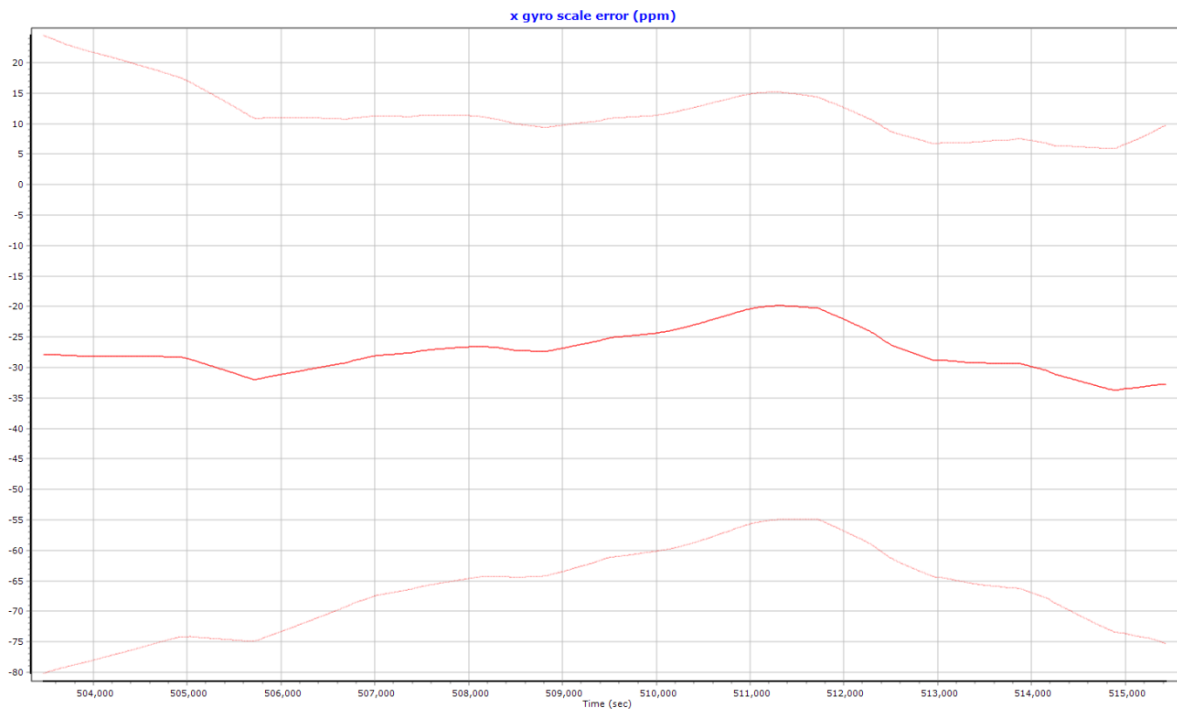
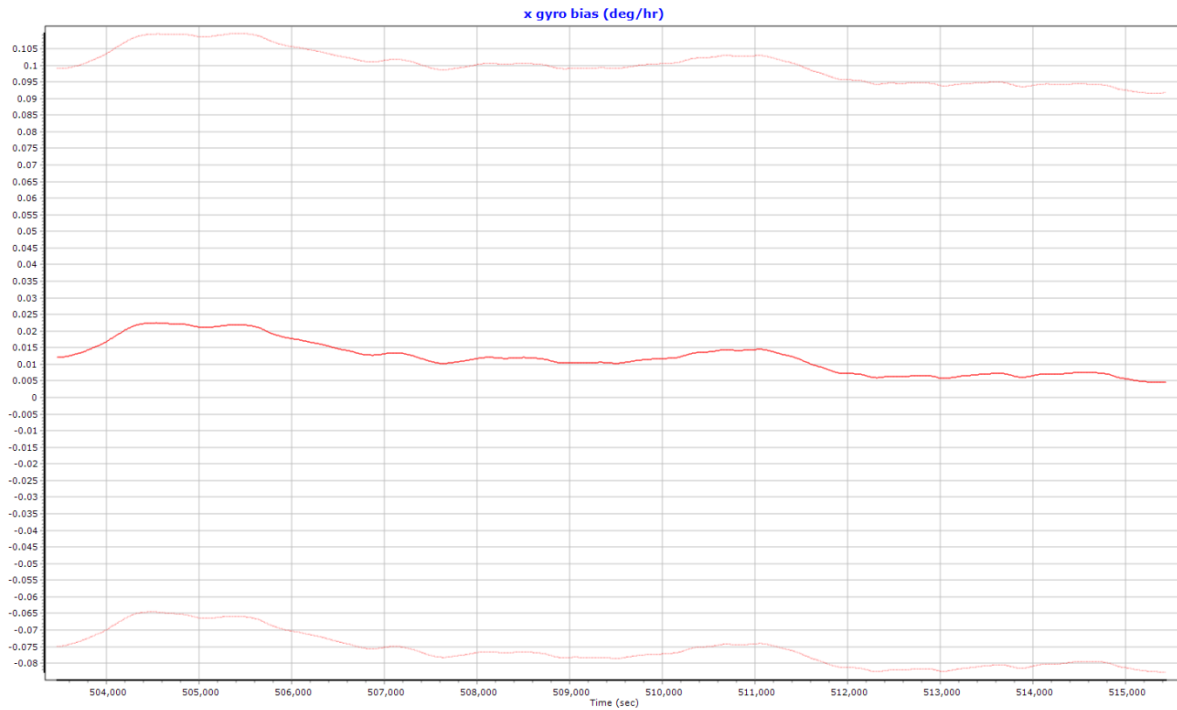
Entire time interval
 Seconds of start week

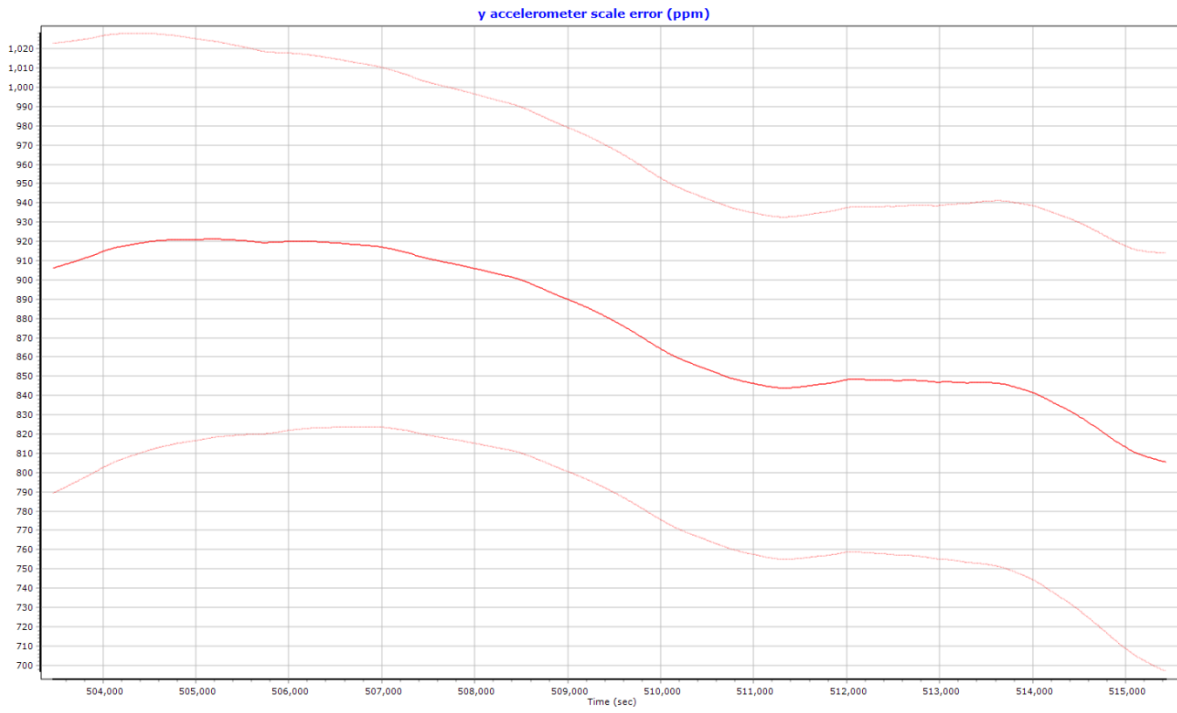
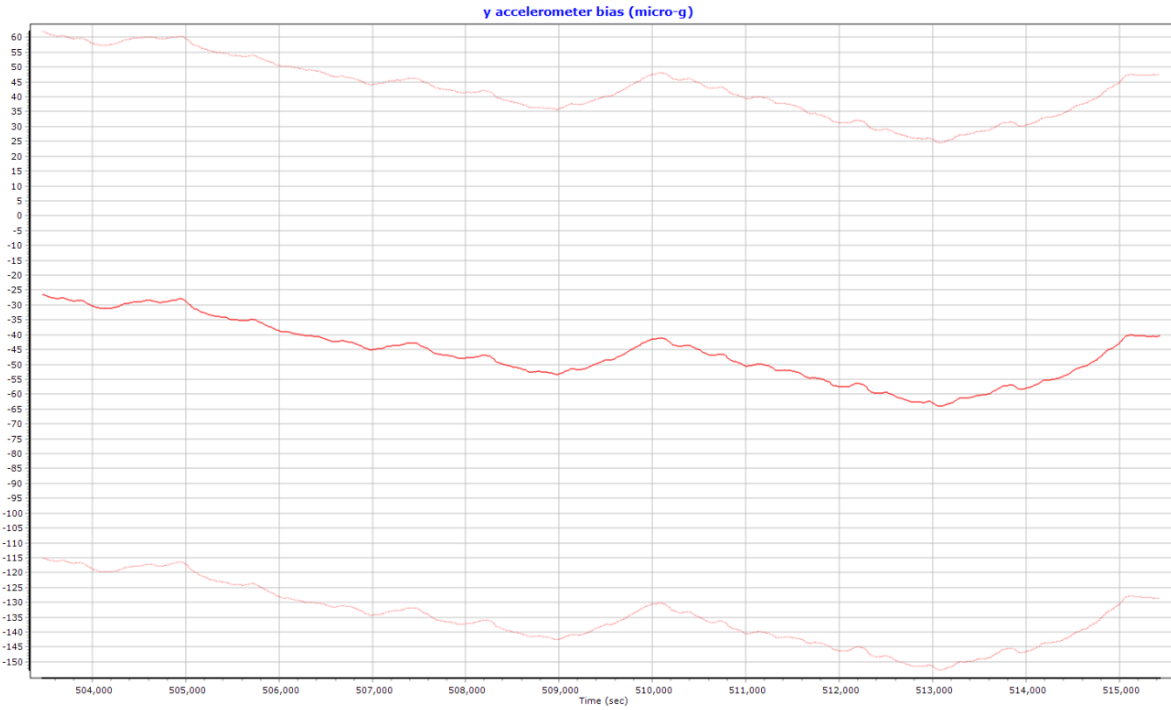
UTC Offset: 18.000

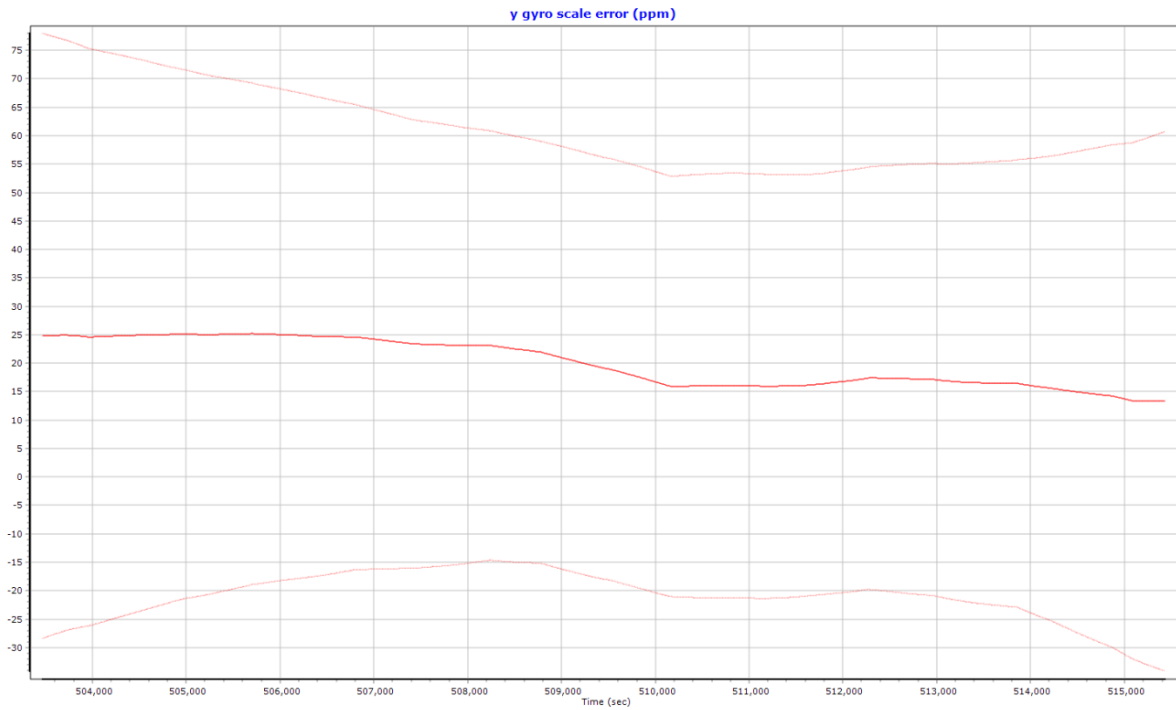
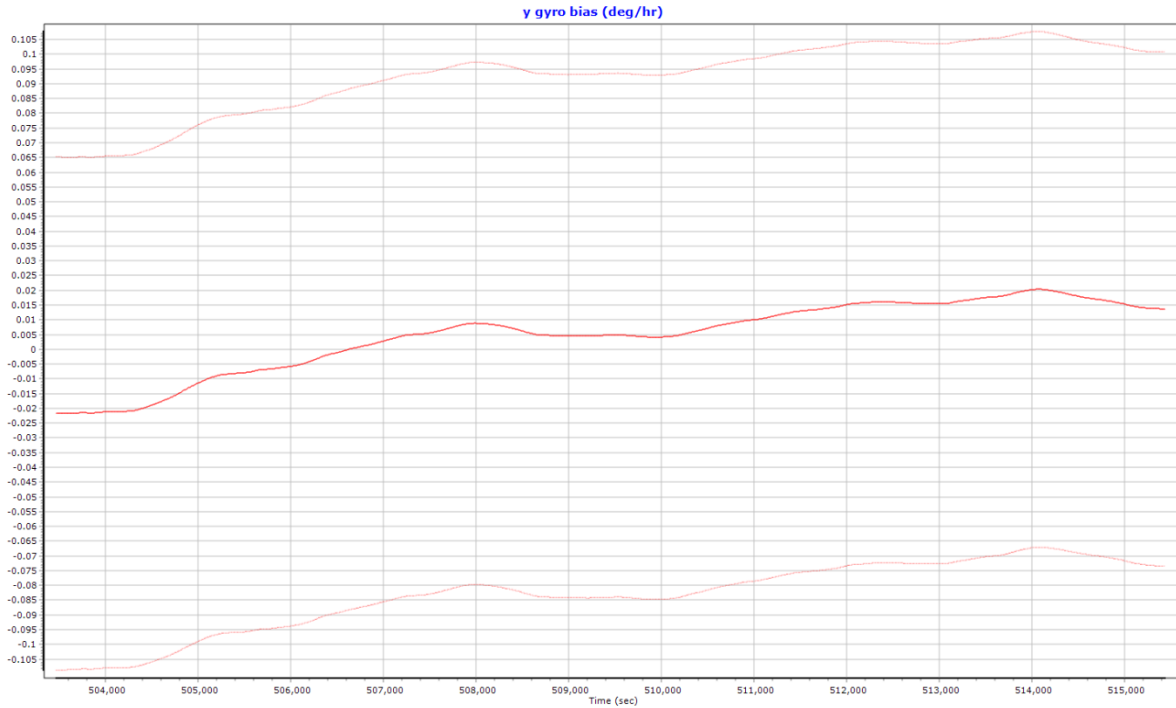
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

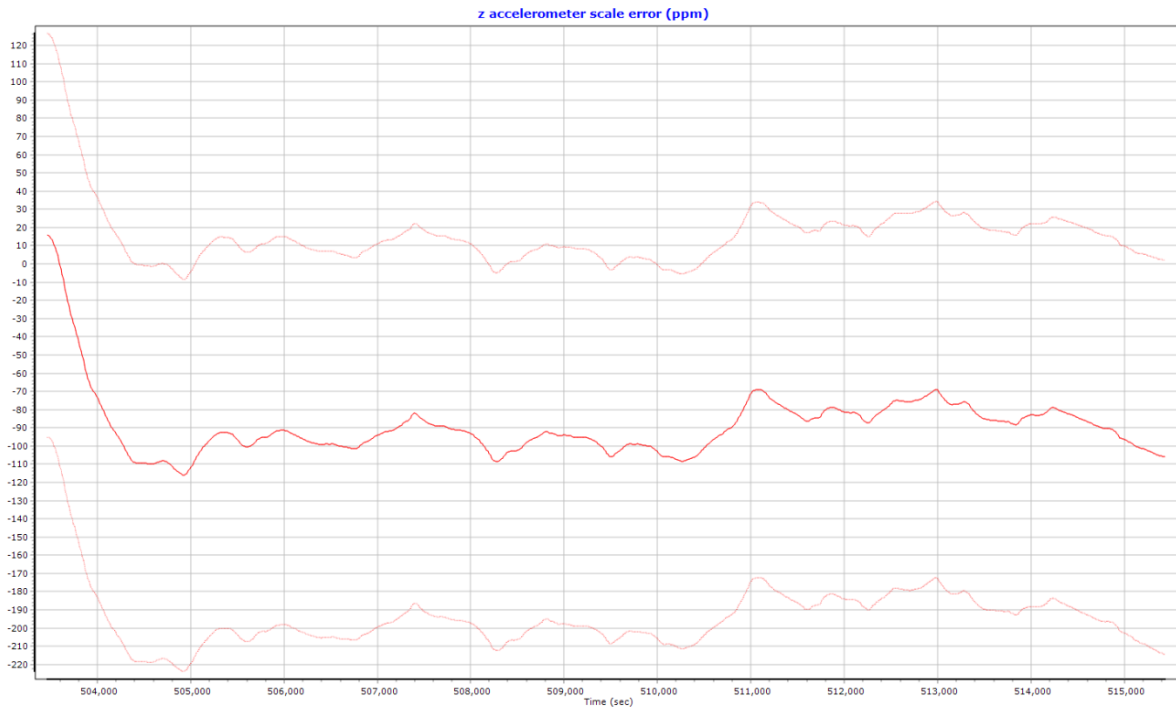
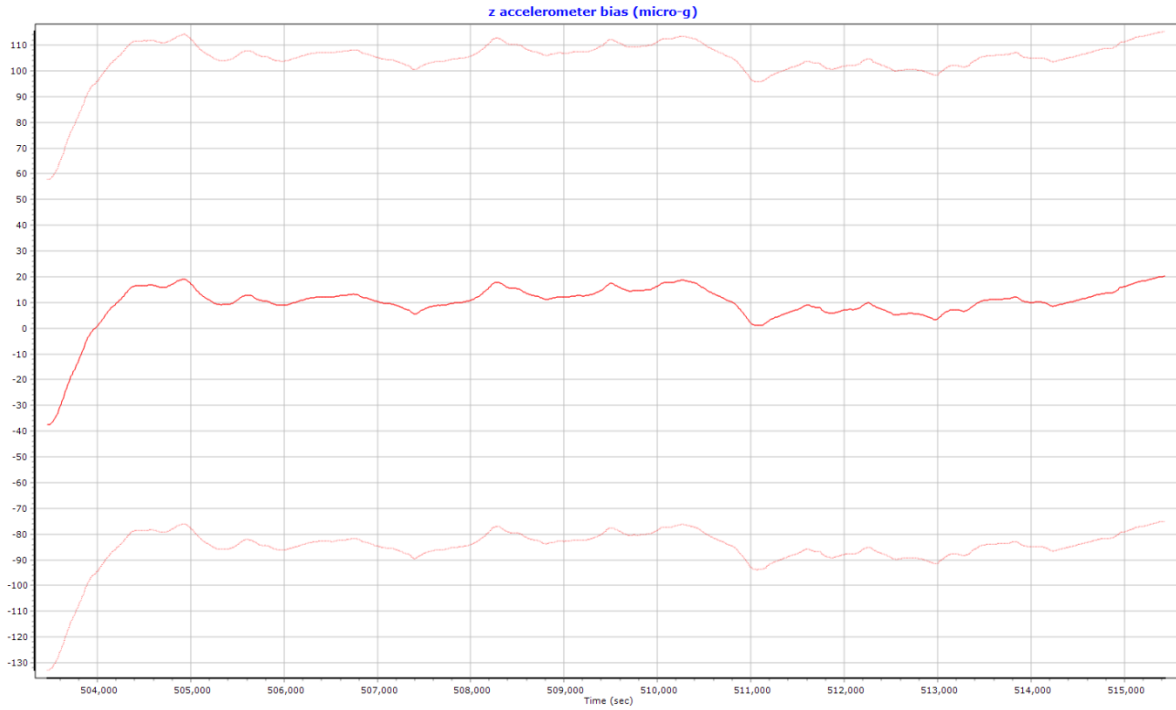
OK Cancel

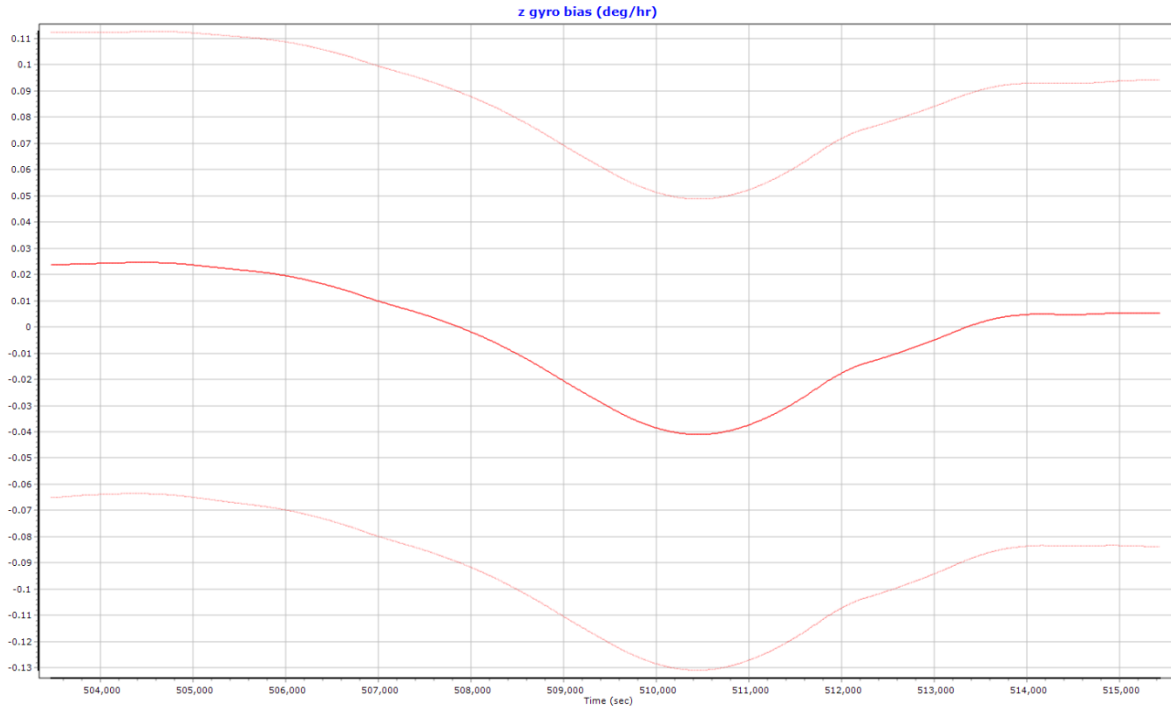




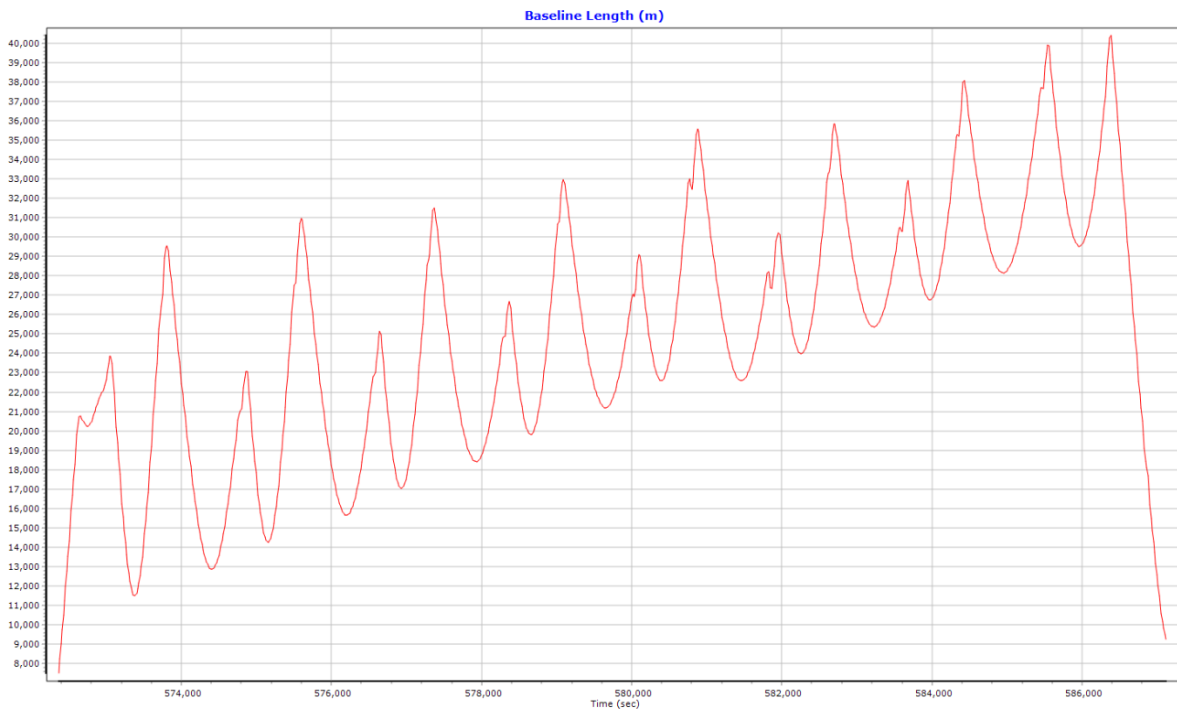
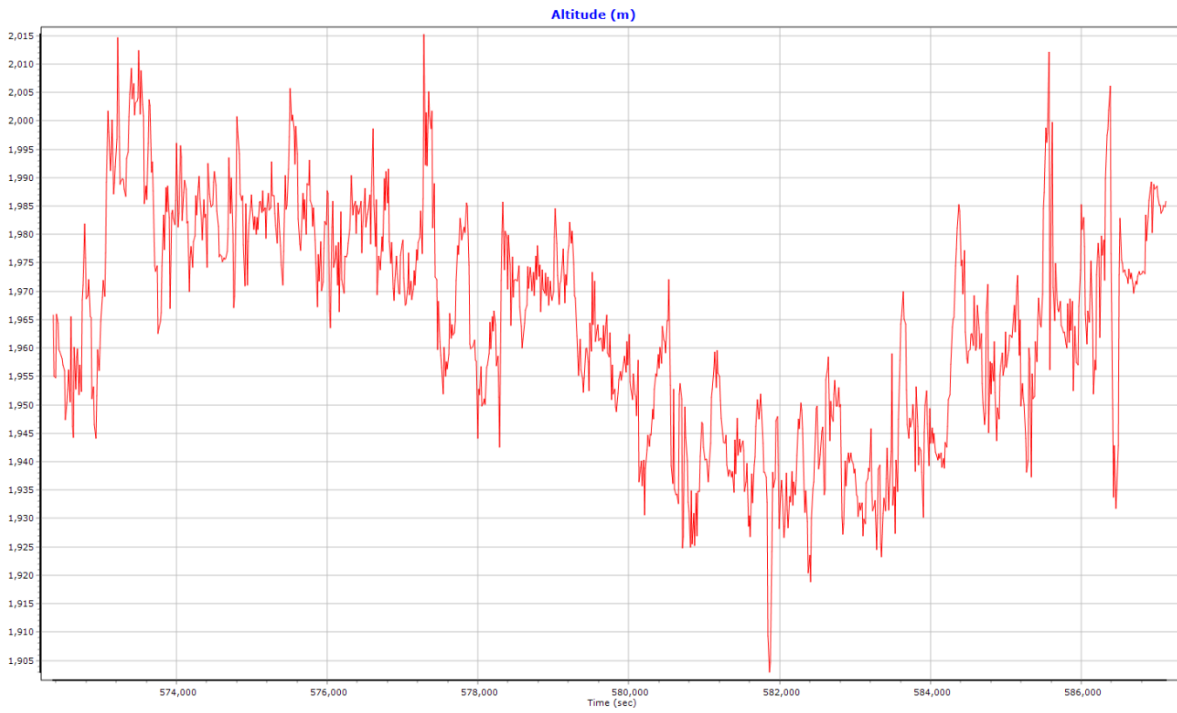


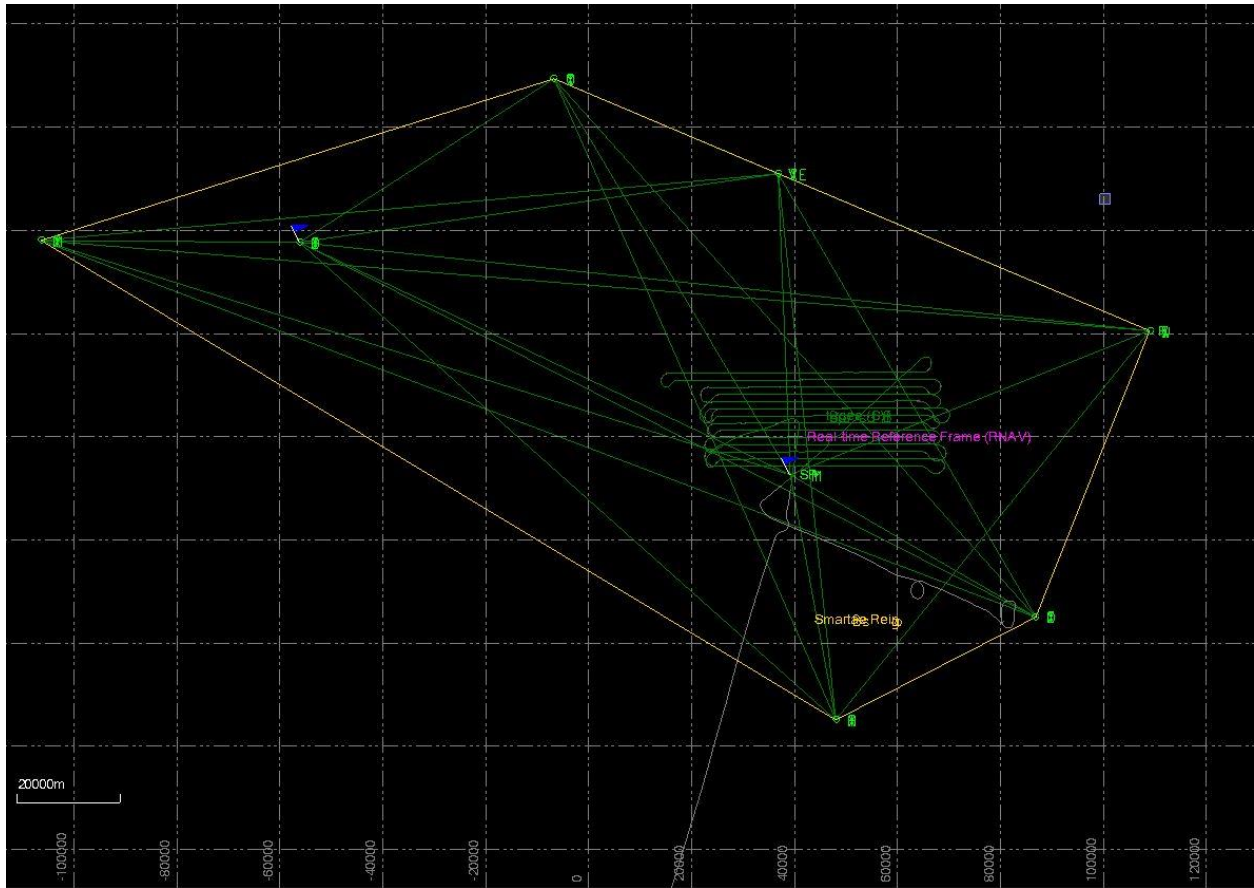






RBV18069A





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	0.000 m
Y	0.000 m
Z	0.000 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	-0.031 m
Y	0.004 m
Z	-0.611 m

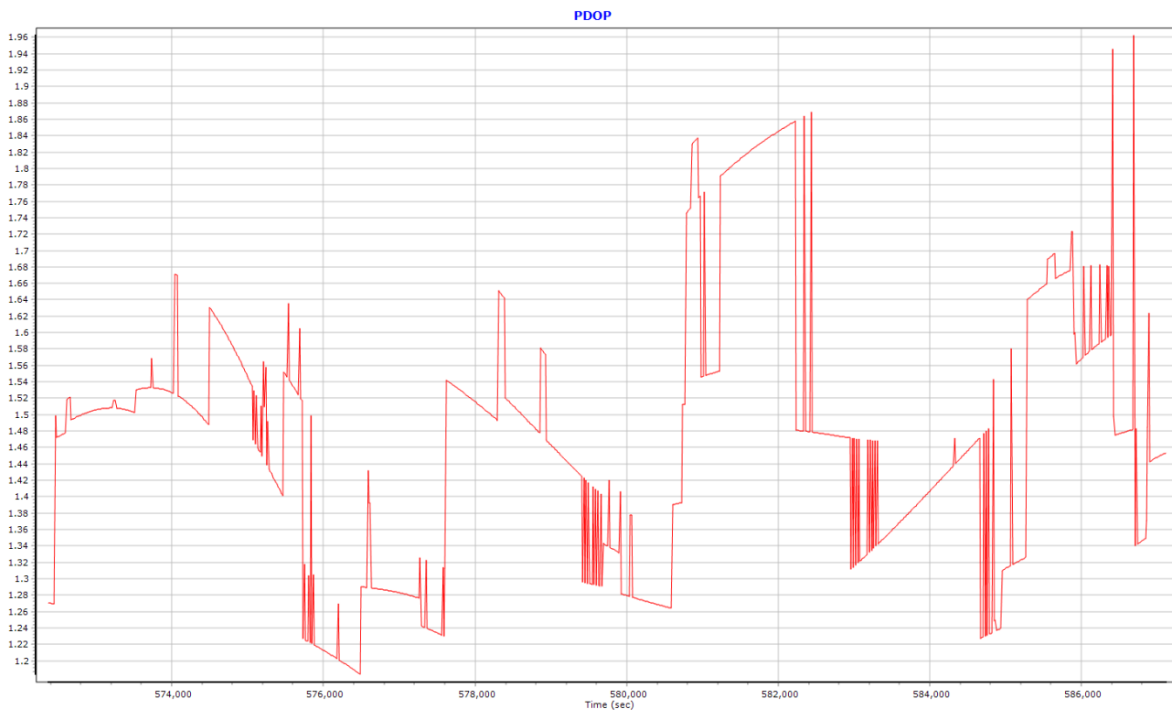
Aircraft to Stabilized Mount Mounting Angles

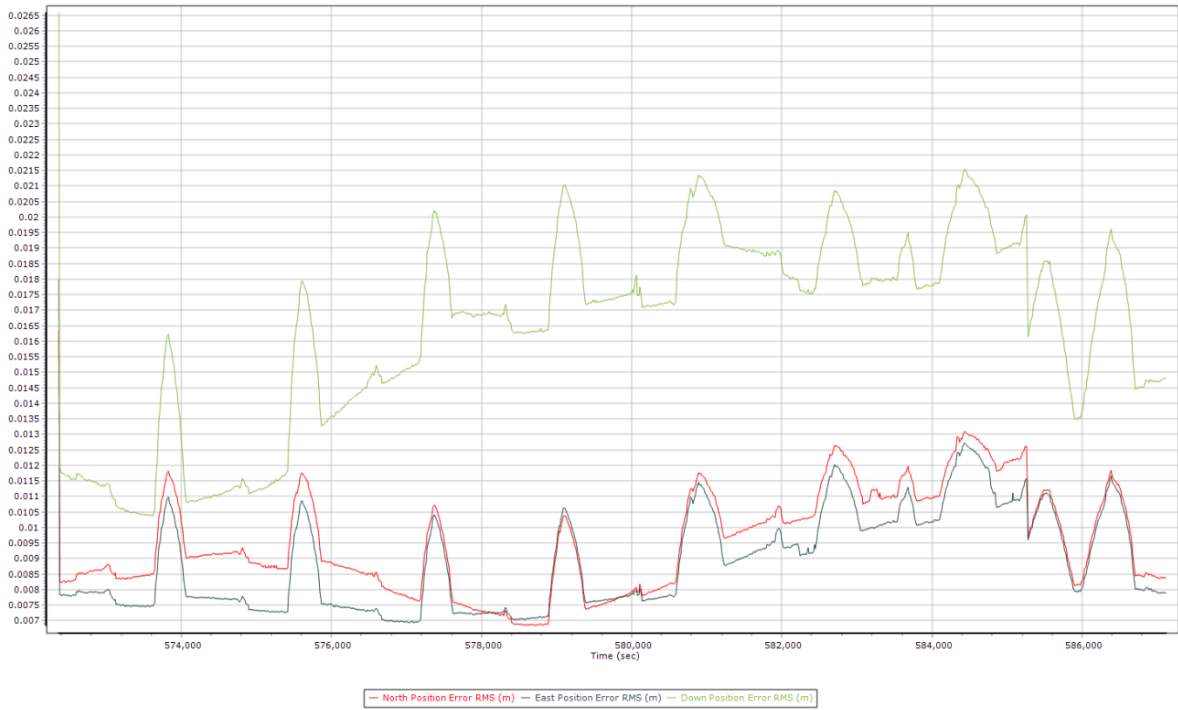
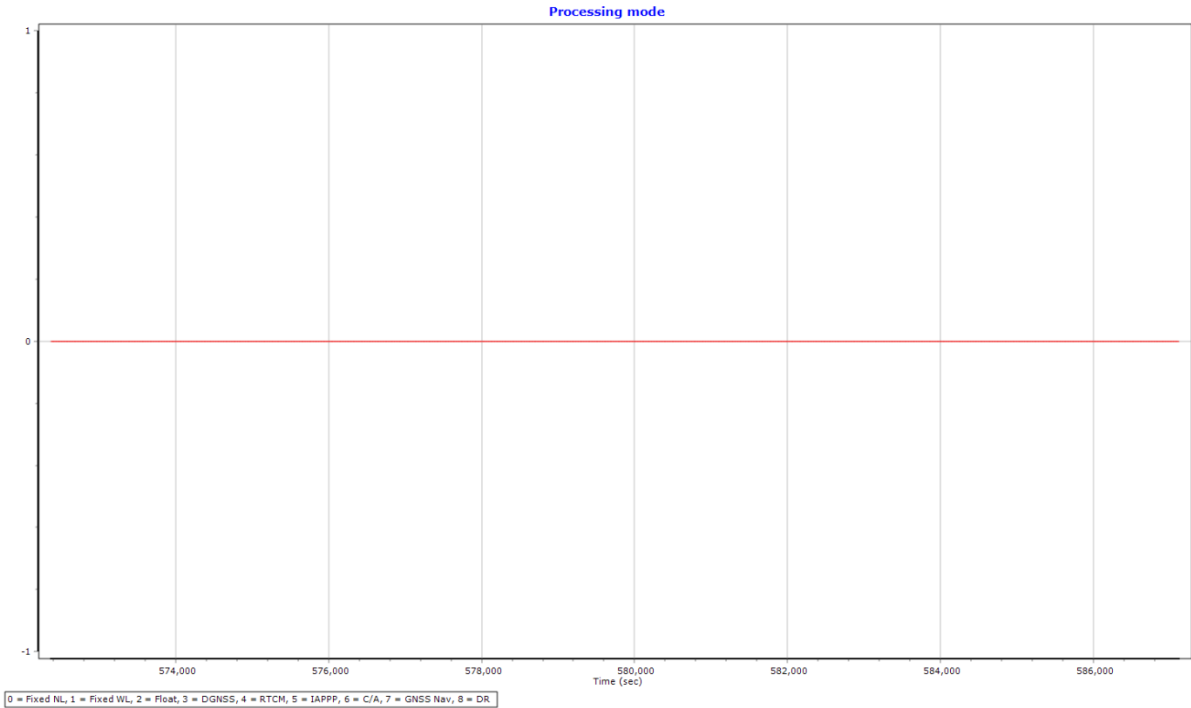
X	0.000 deg
Y	0.000 deg
Z	0.000 deg

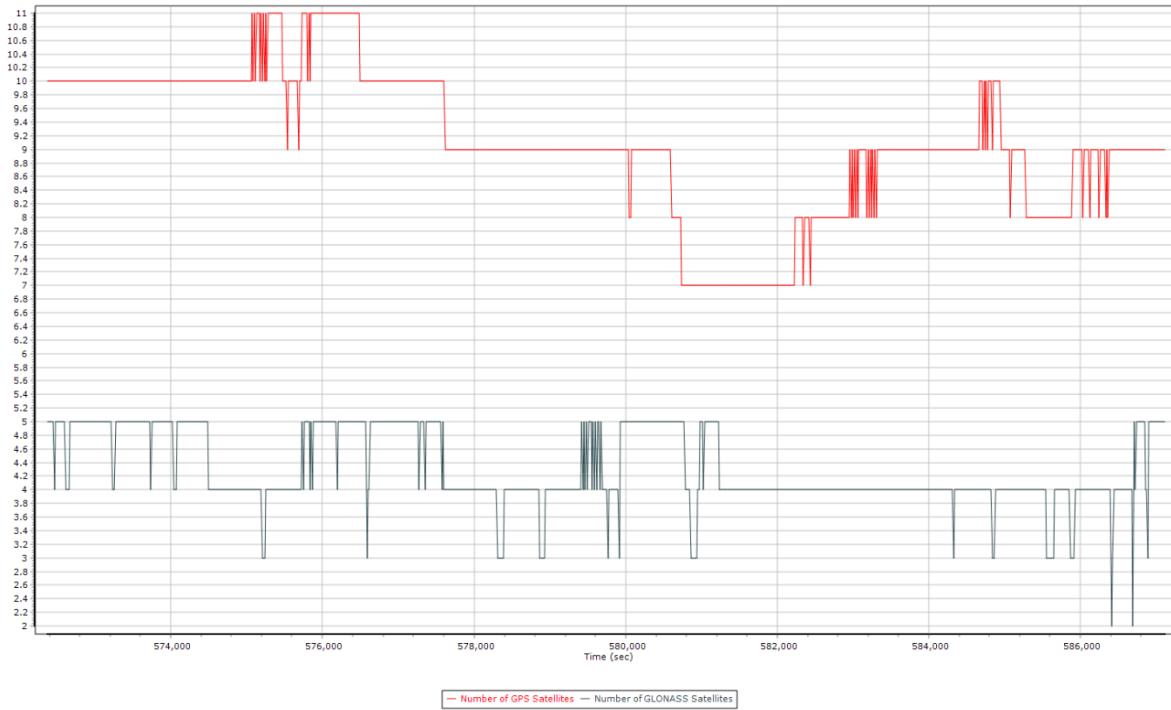
Standard Deviation: <3cm 10cm 50cm 1m 10m

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

OK Cancel







Project Settings [X]

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

Timing

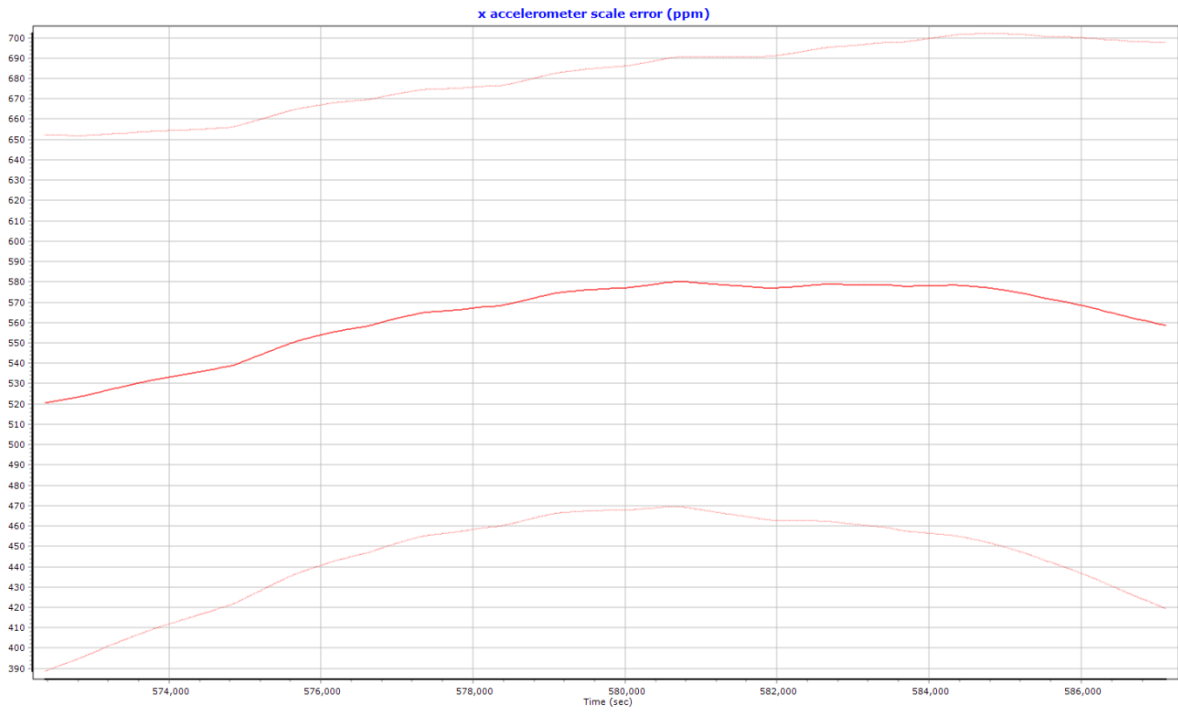
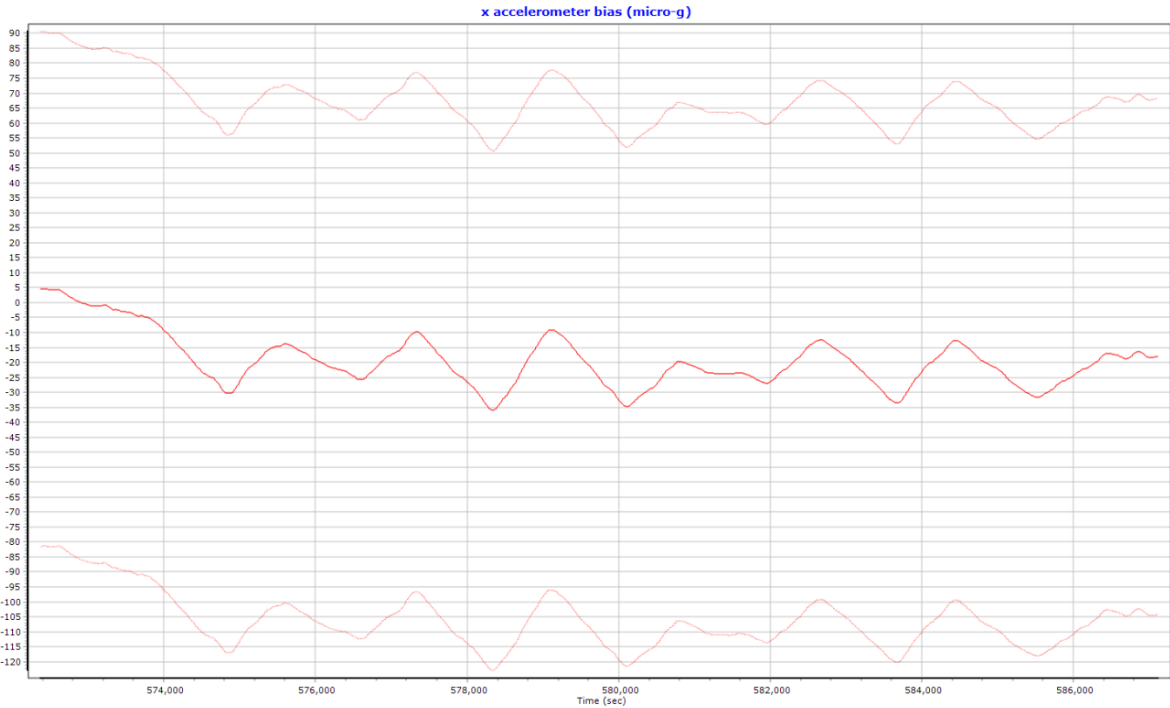
Start: 572367.656 End: 587141.101

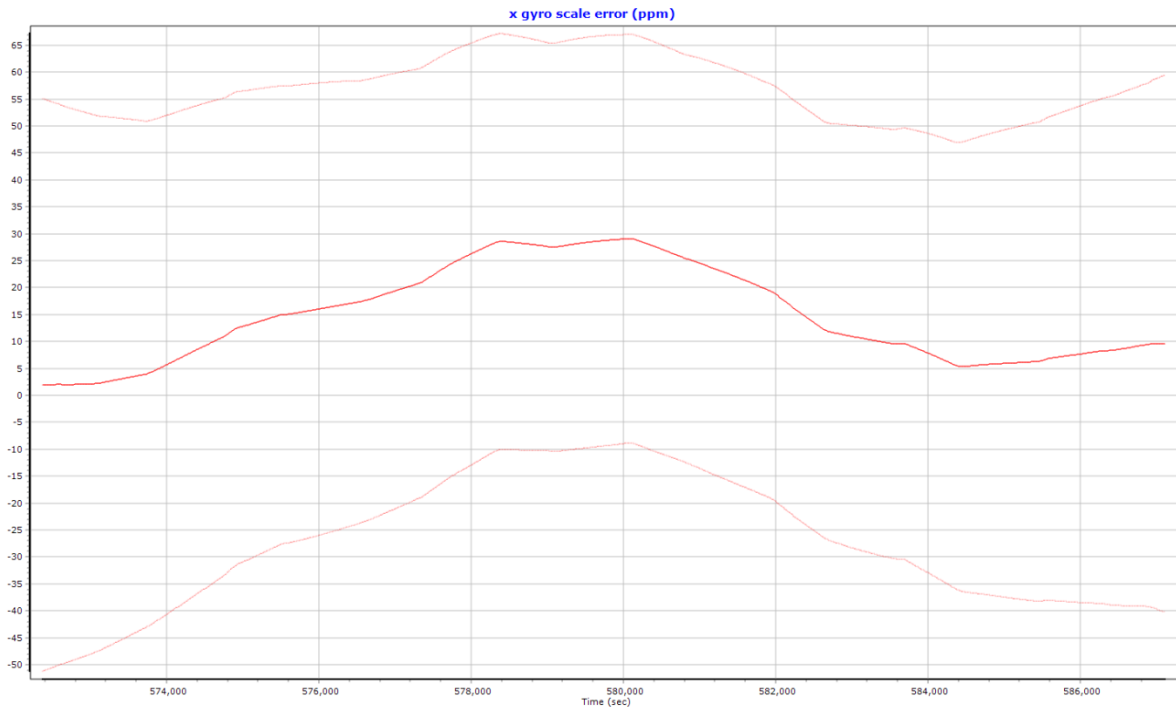
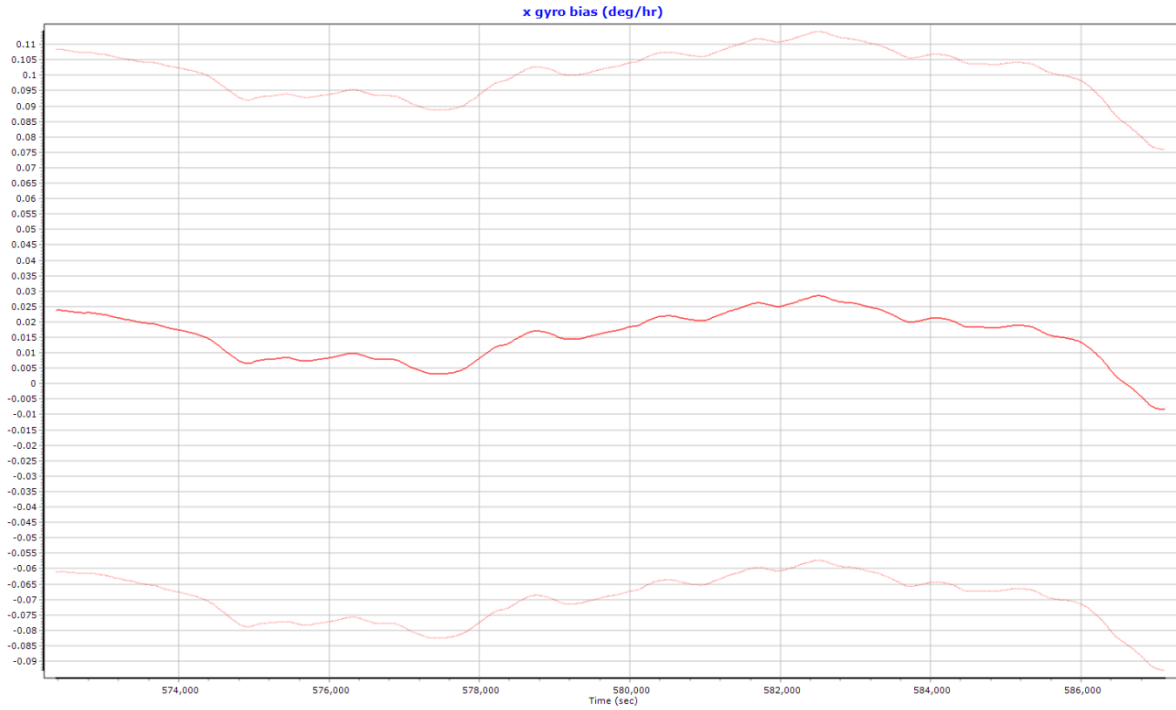
Entire time interval Seconds of start week

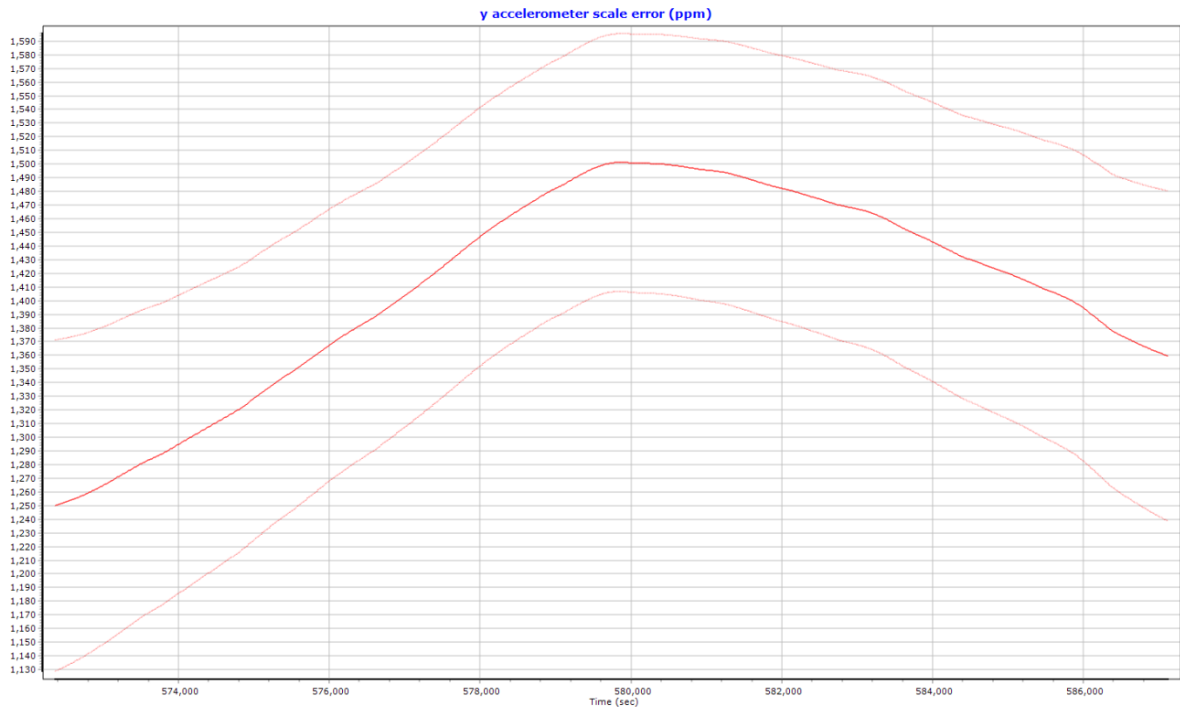
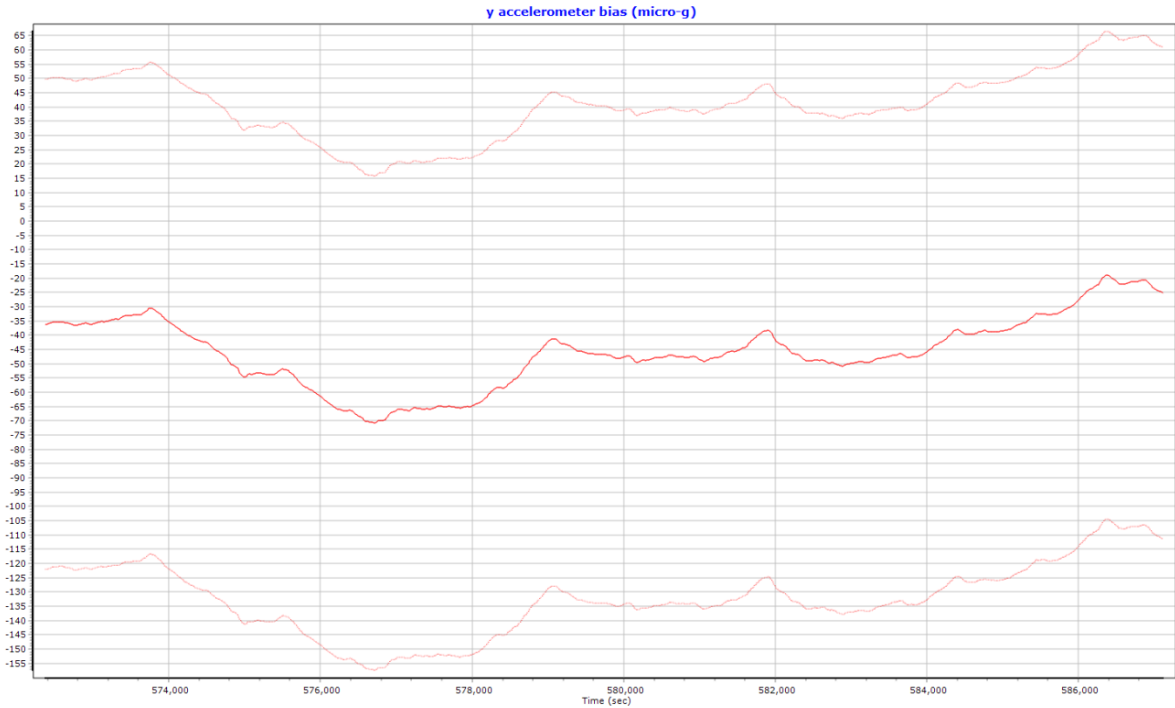
UTC Offset: 18.000

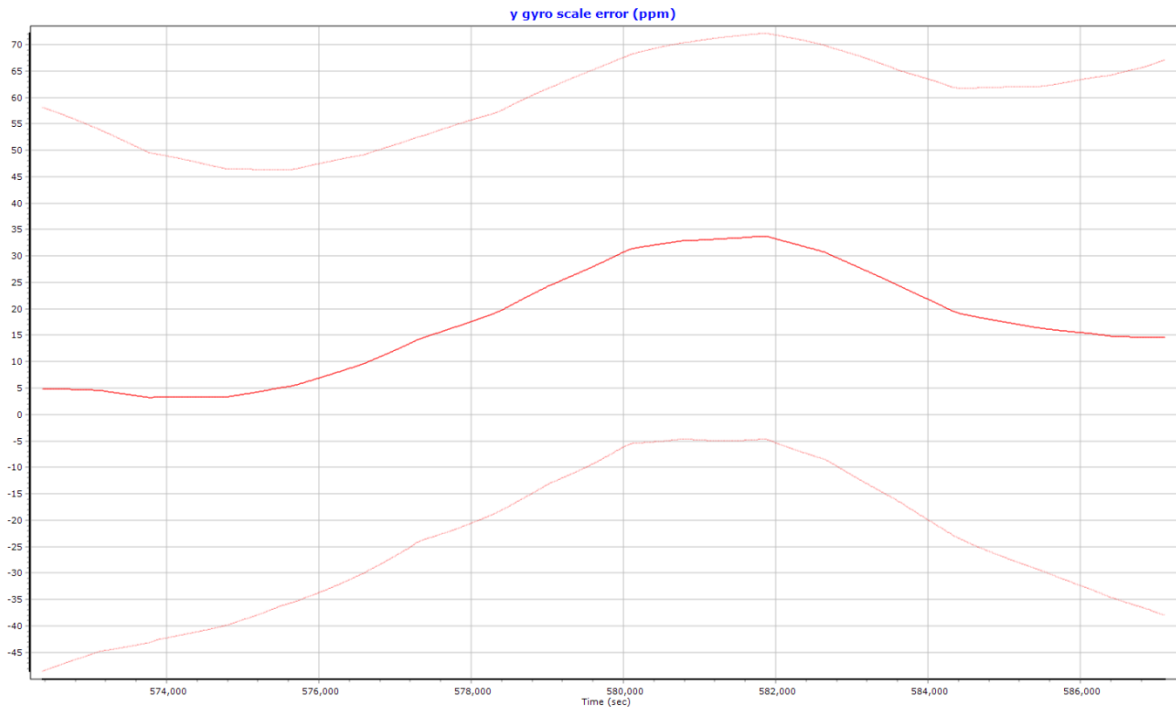
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

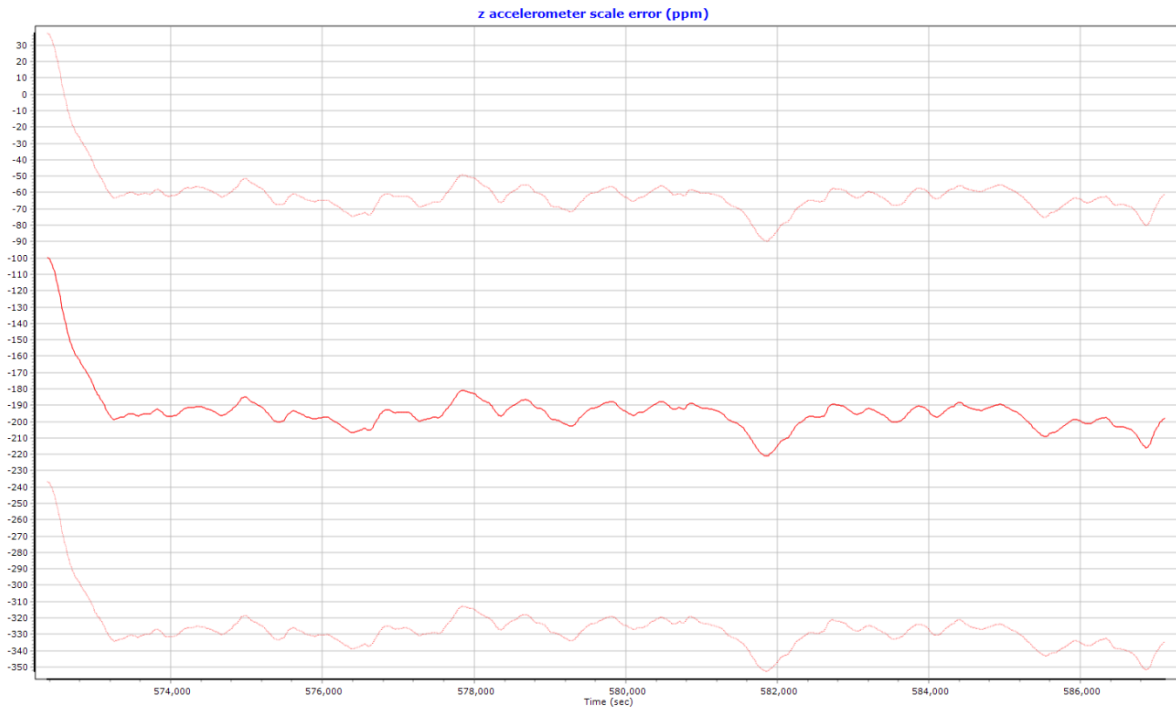
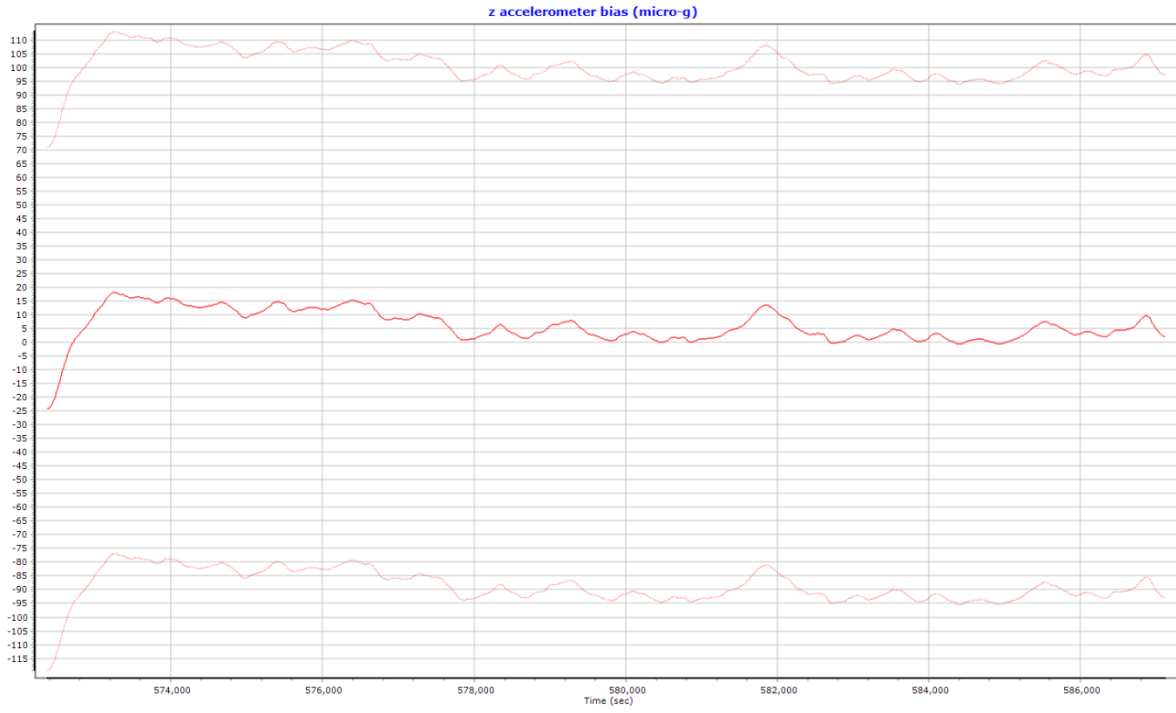
OK Cancel

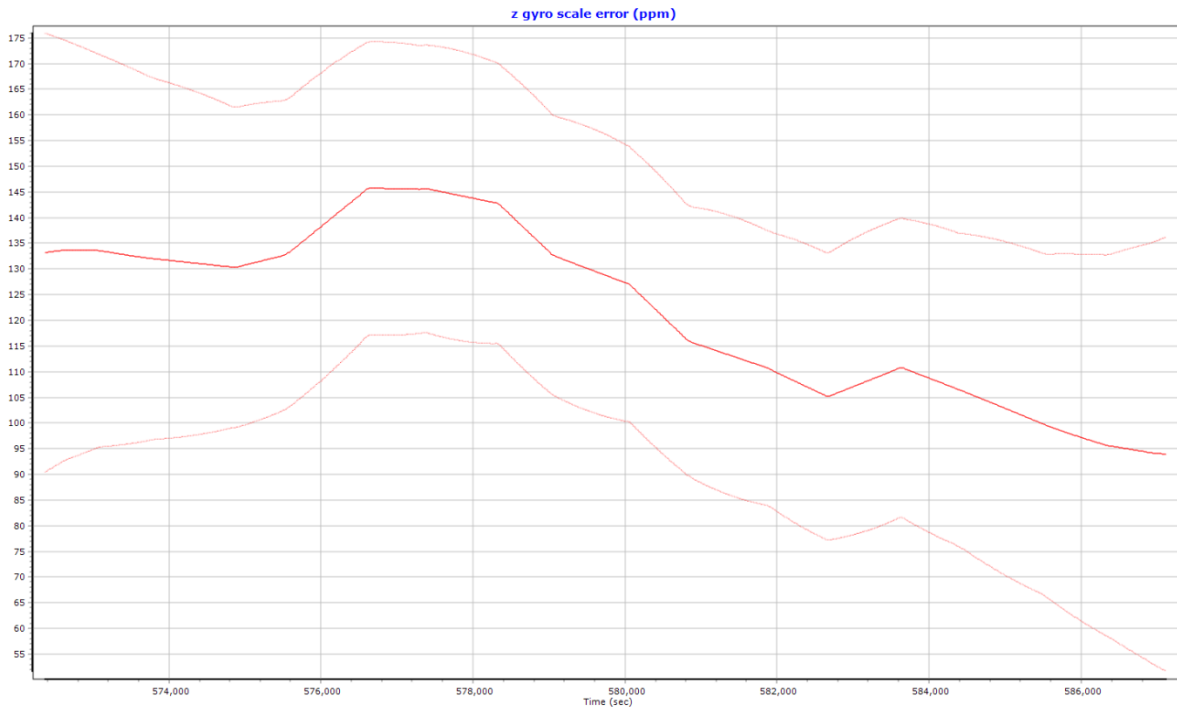
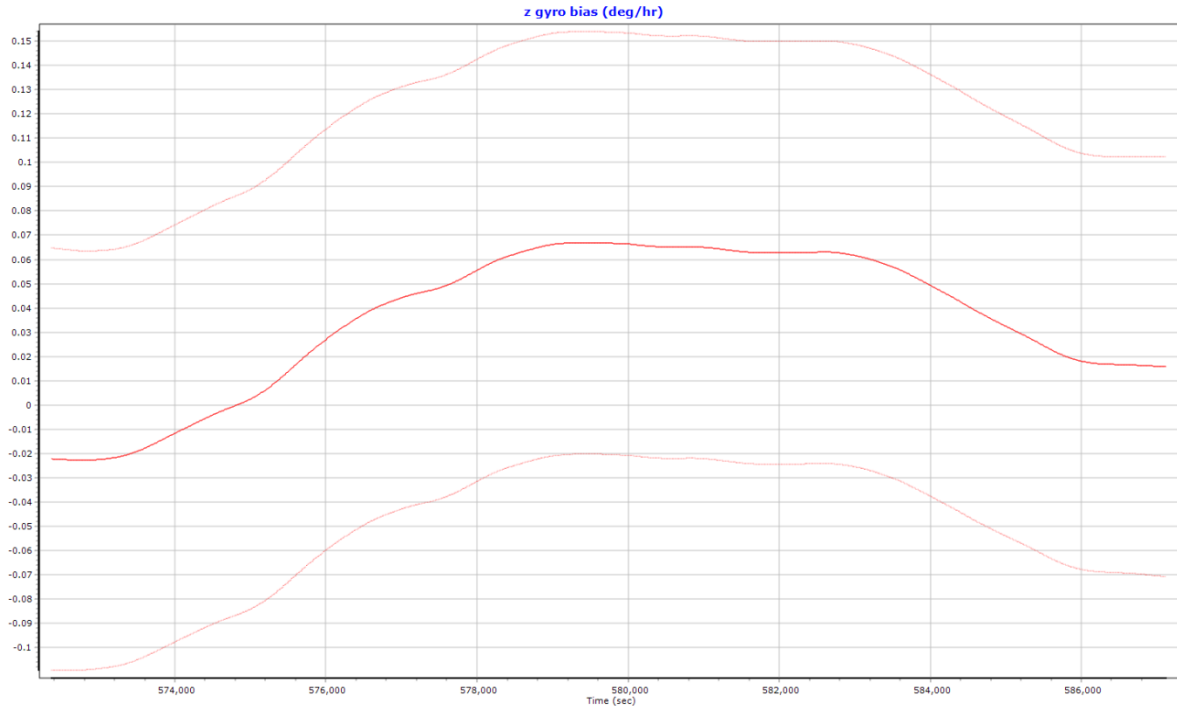




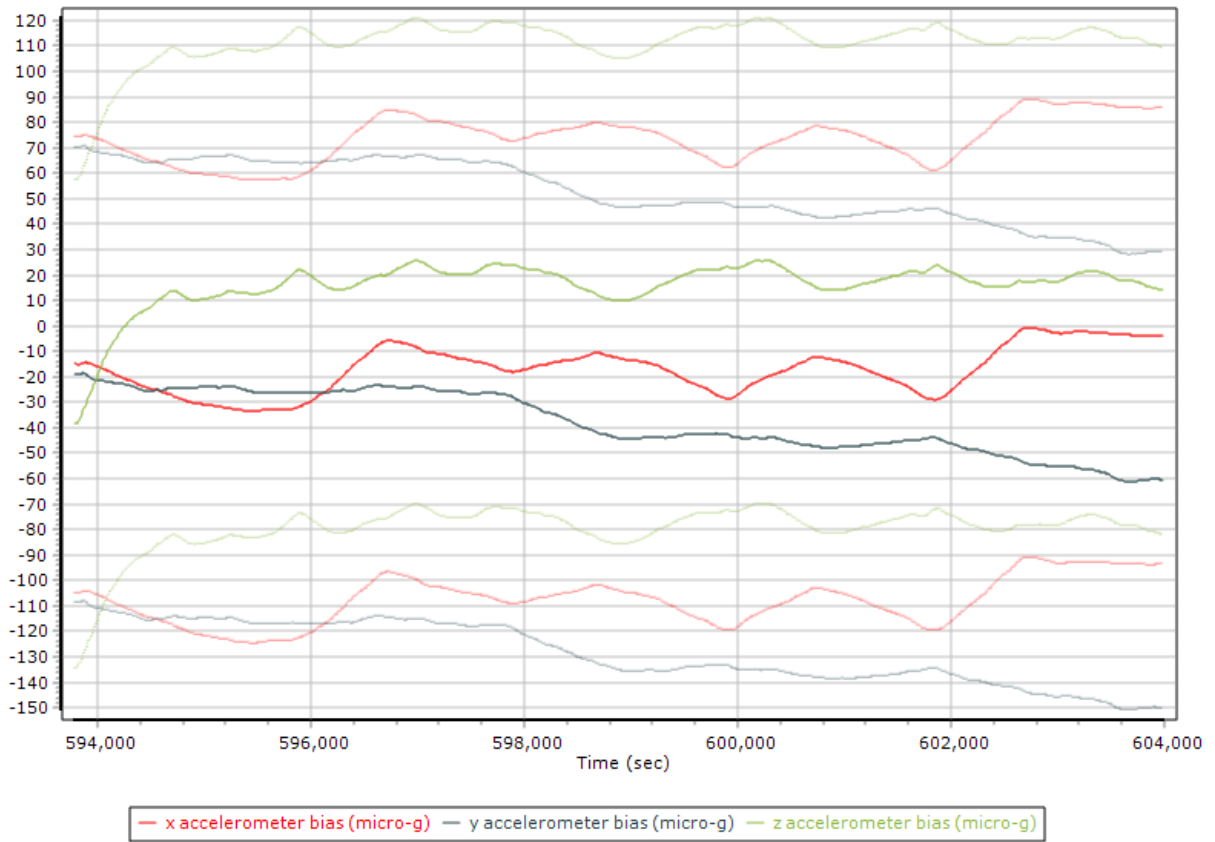


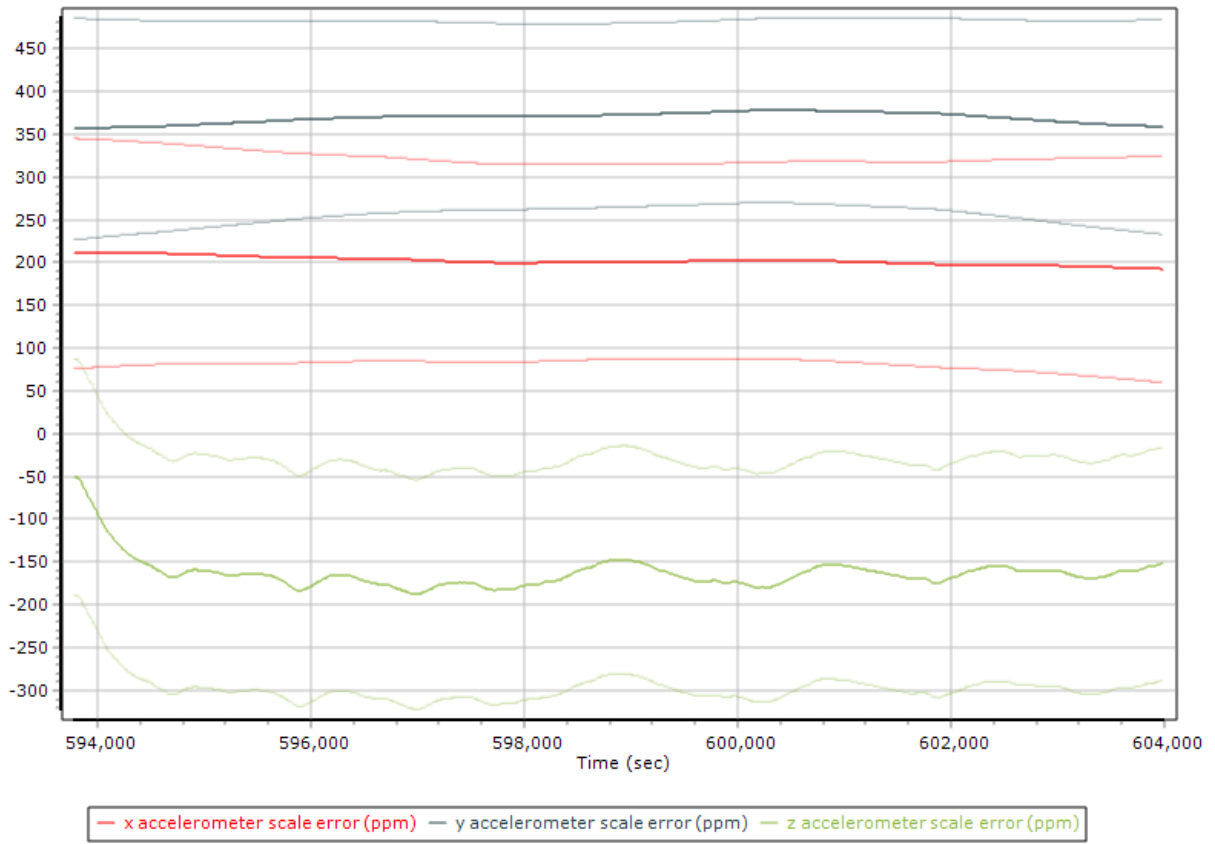


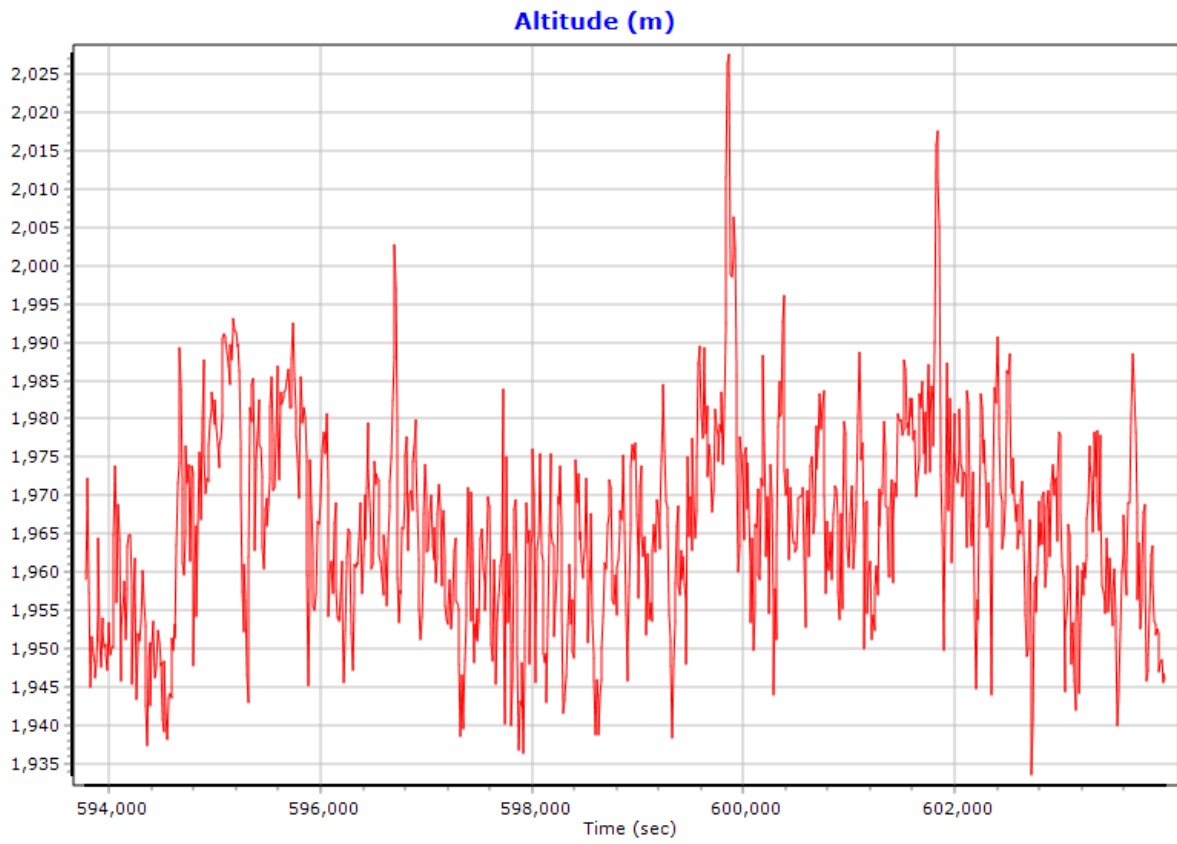




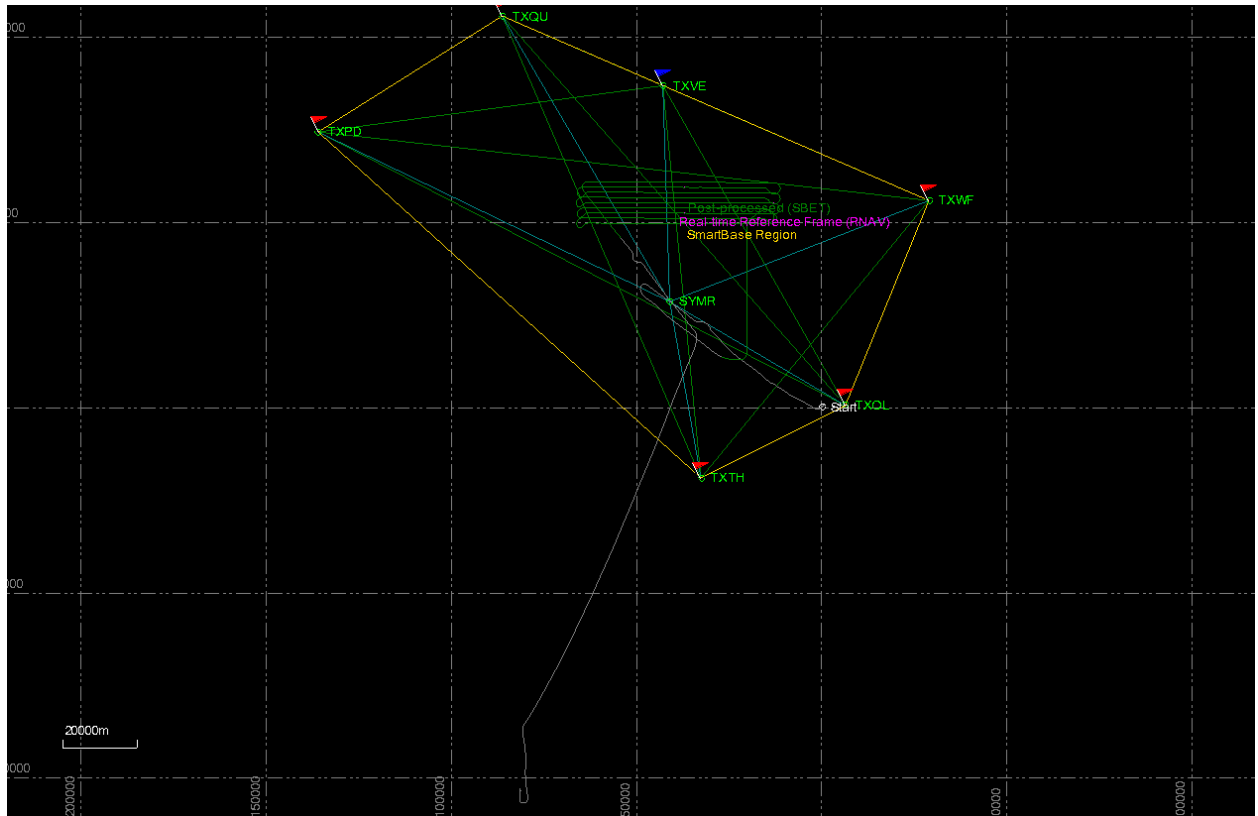
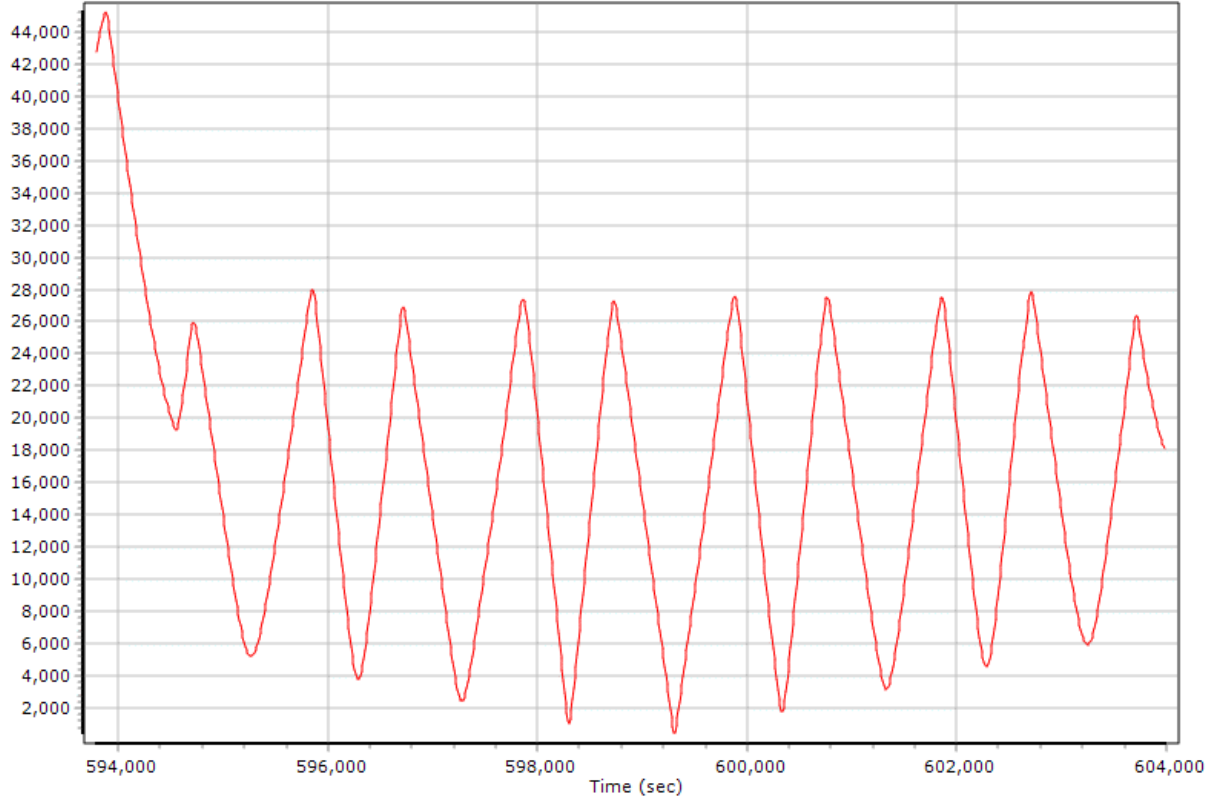
RBV18069B

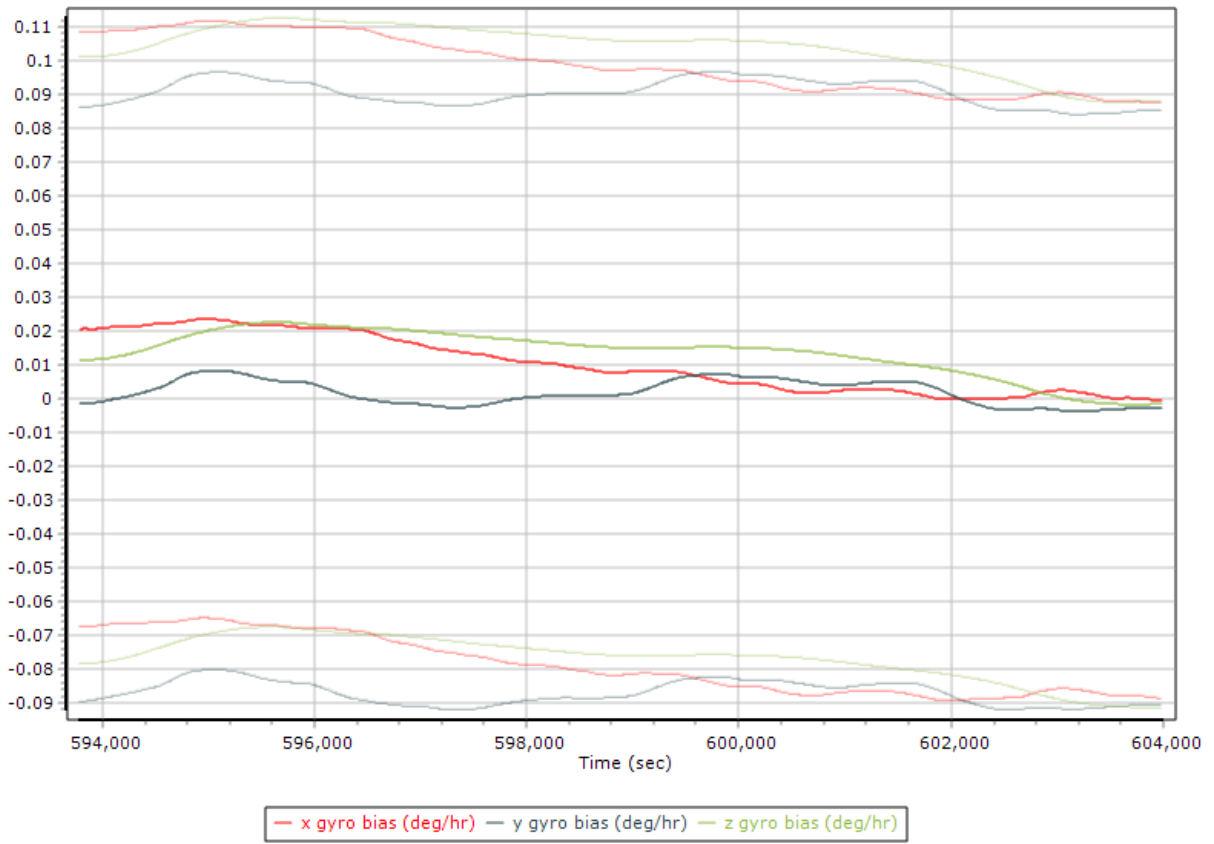


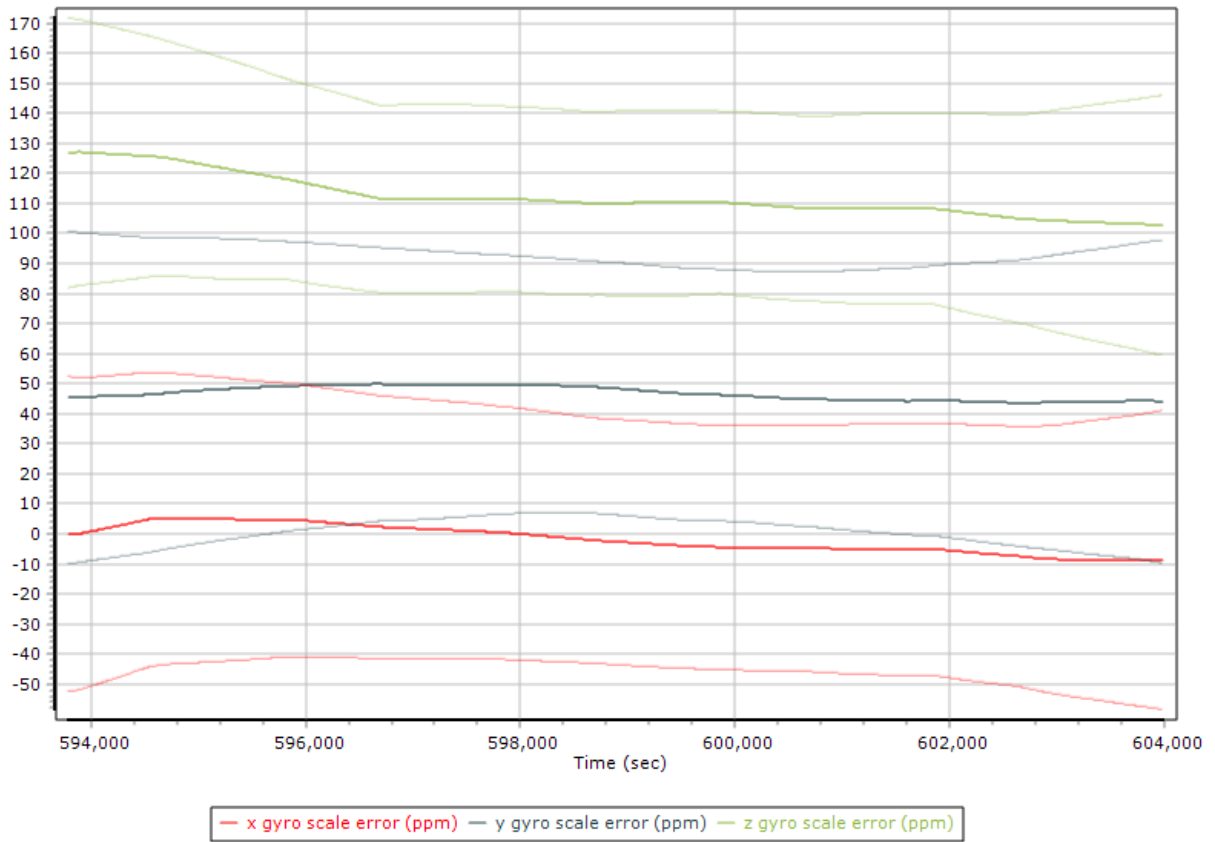




Baseline Length (m)







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:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

Aircraft to Stabilized Mount Mounting Angles

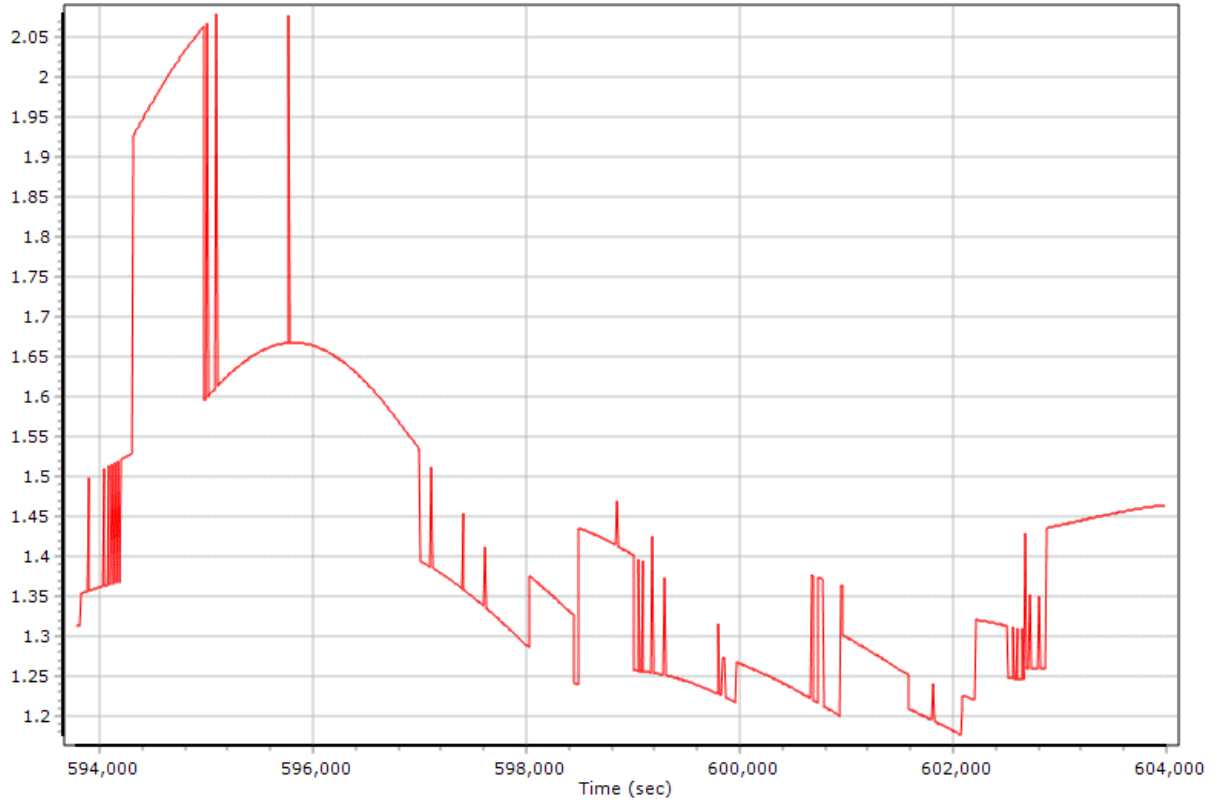
X:

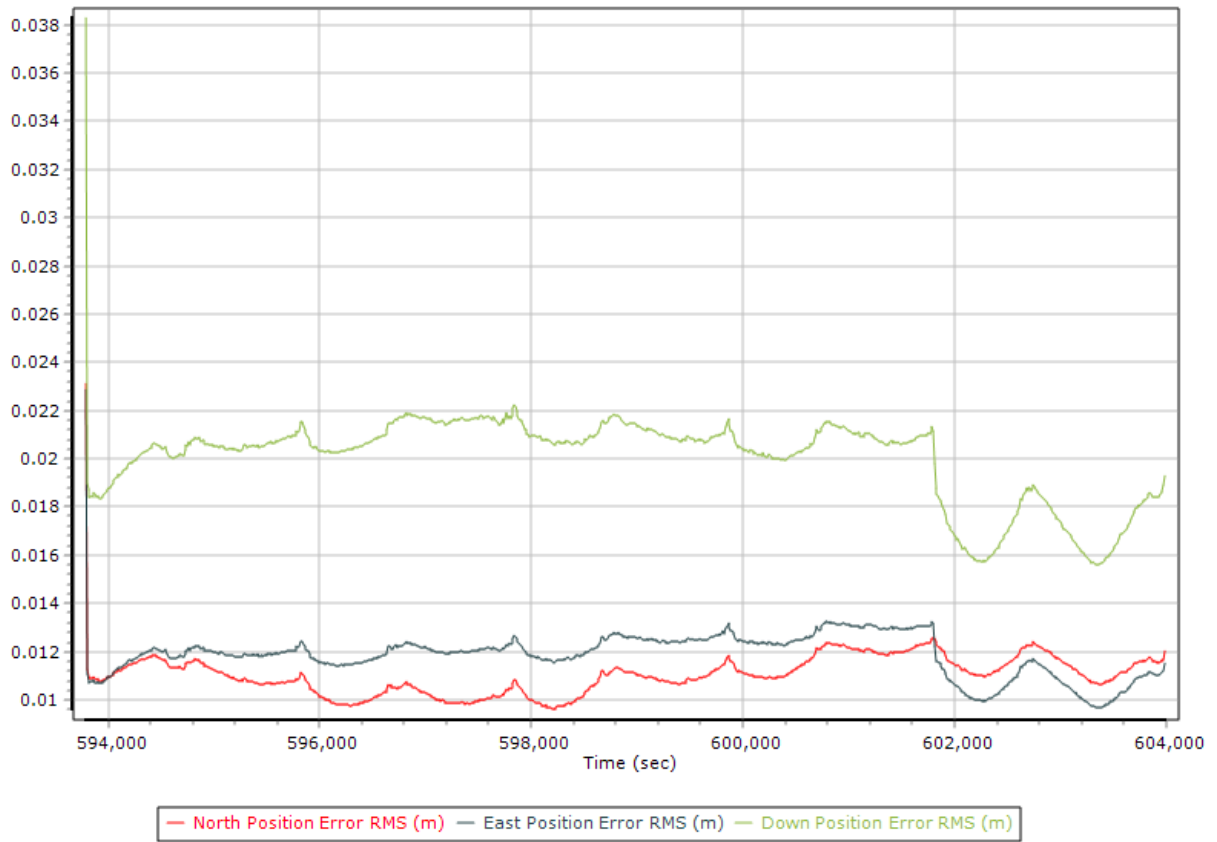
Y:

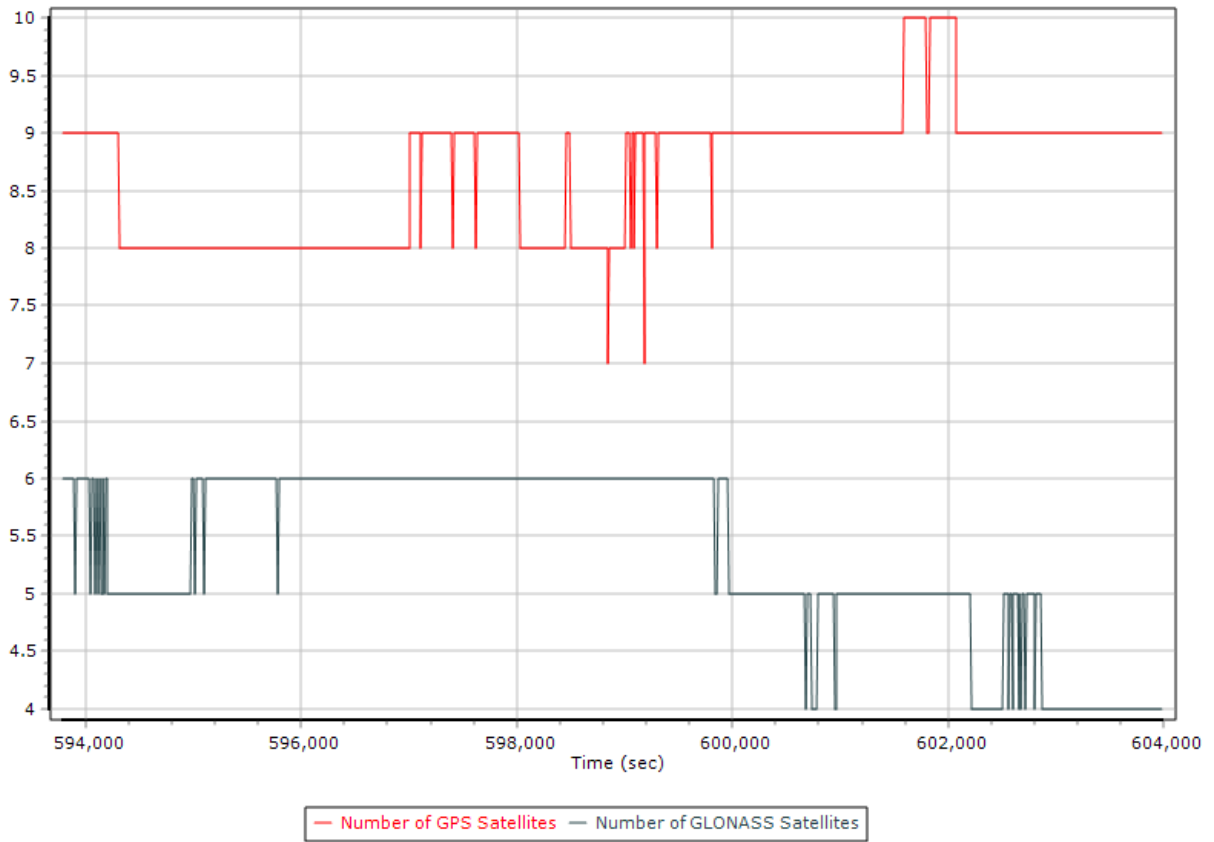
Z:

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

PDOP







Project Settings [X]

- General Information
- Units
- View
- Rover Import
- Satellite Selection**
- GNSS-Inertial Processor
- Export
- Camera
- LIDAR
- SAR

Disable Satellites

GPS | **GLONASS** | BEIDOU | QZSS

<input type="checkbox"/> PRN 1	<input type="checkbox"/> PRN 10	<input type="checkbox"/> PRN 19	<input type="checkbox"/> PRN 28
<input type="checkbox"/> PRN 2	<input type="checkbox"/> PRN 11	<input type="checkbox"/> PRN 20	<input type="checkbox"/> PRN 29
<input type="checkbox"/> PRN 3	<input type="checkbox"/> PRN 12	<input type="checkbox"/> PRN 21	<input type="checkbox"/> PRN 30
<input type="checkbox"/> PRN 4	<input type="checkbox"/> PRN 13	<input type="checkbox"/> PRN 22	<input type="checkbox"/> PRN 31
<input type="checkbox"/> PRN 5	<input type="checkbox"/> PRN 14	<input type="checkbox"/> PRN 23	<input type="checkbox"/> PRN 32
<input type="checkbox"/> PRN 6	<input type="checkbox"/> PRN 15	<input type="checkbox"/> PRN 24	
<input type="checkbox"/> PRN 7	<input type="checkbox"/> PRN 16	<input type="checkbox"/> PRN 25	
<input type="checkbox"/> PRN 8	<input type="checkbox"/> PRN 17	<input type="checkbox"/> PRN 26	
<input type="checkbox"/> PRN 9	<input type="checkbox"/> PRN 18	<input type="checkbox"/> PRN 27	

Elevation Mask Angle:

Force GPS Only

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: 593786.861
End: 603997.263

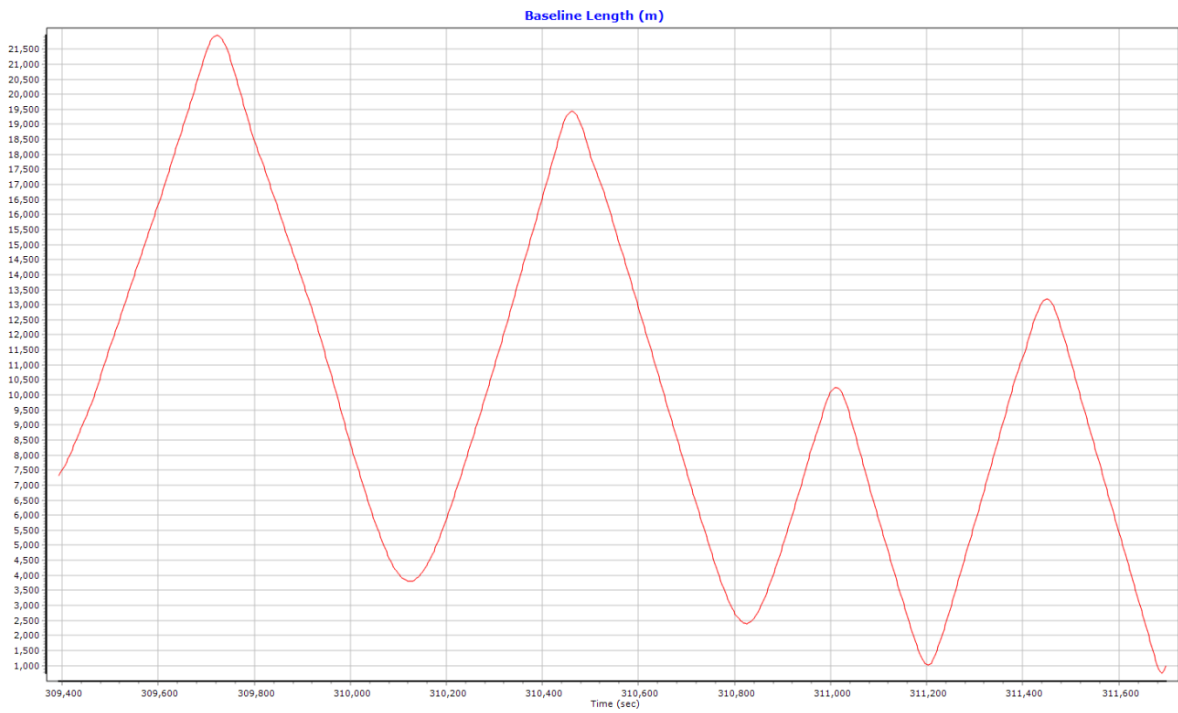
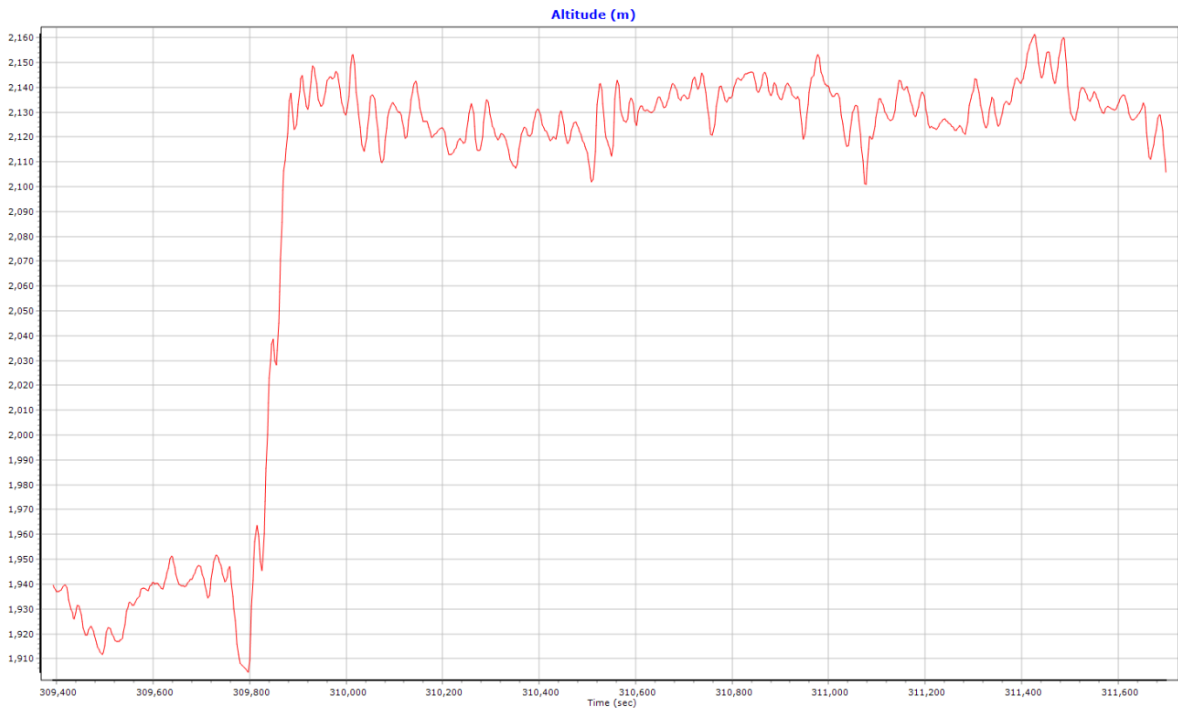
Entire time interval
 Seconds of start week

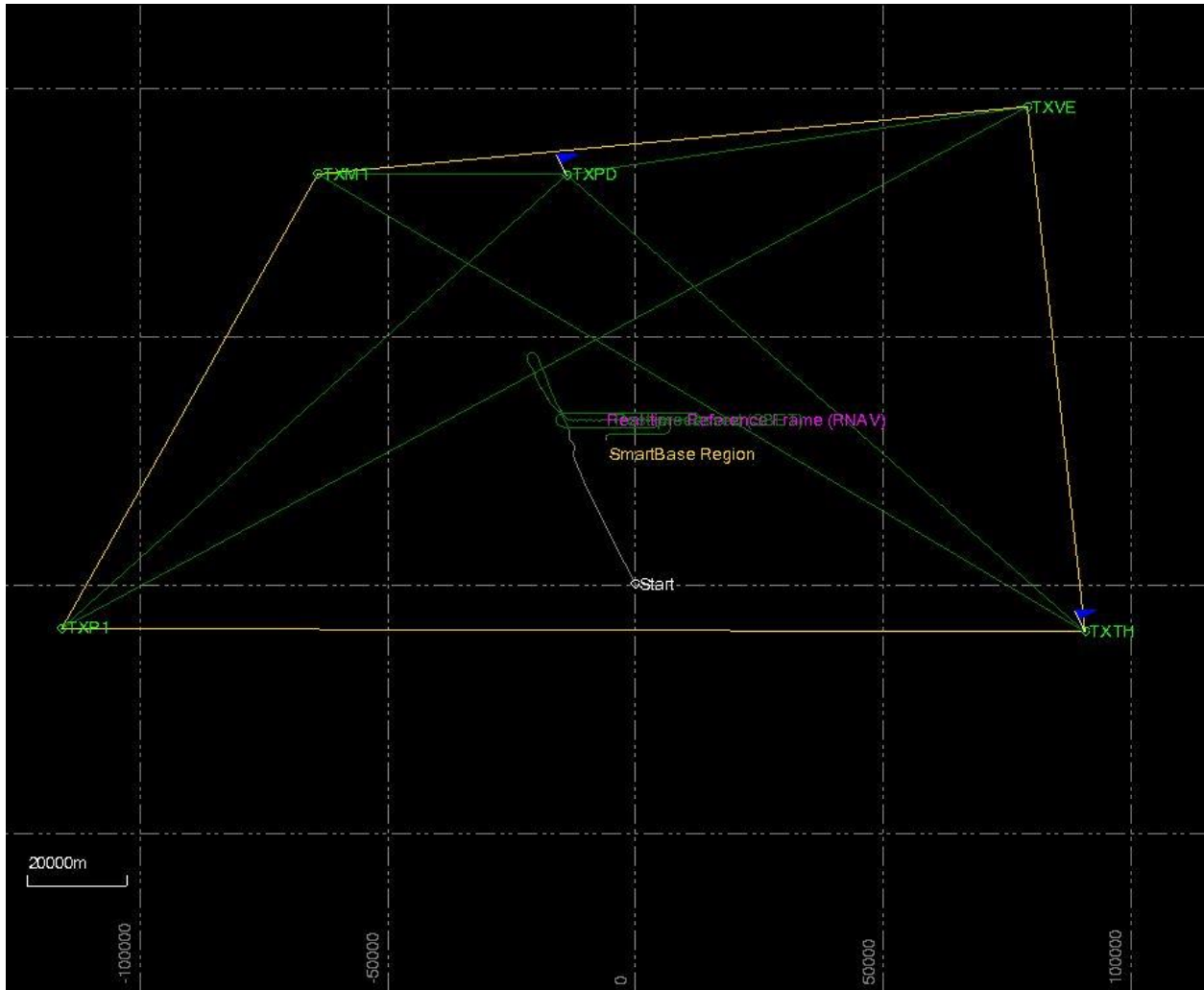
UTC Offset: 18.000

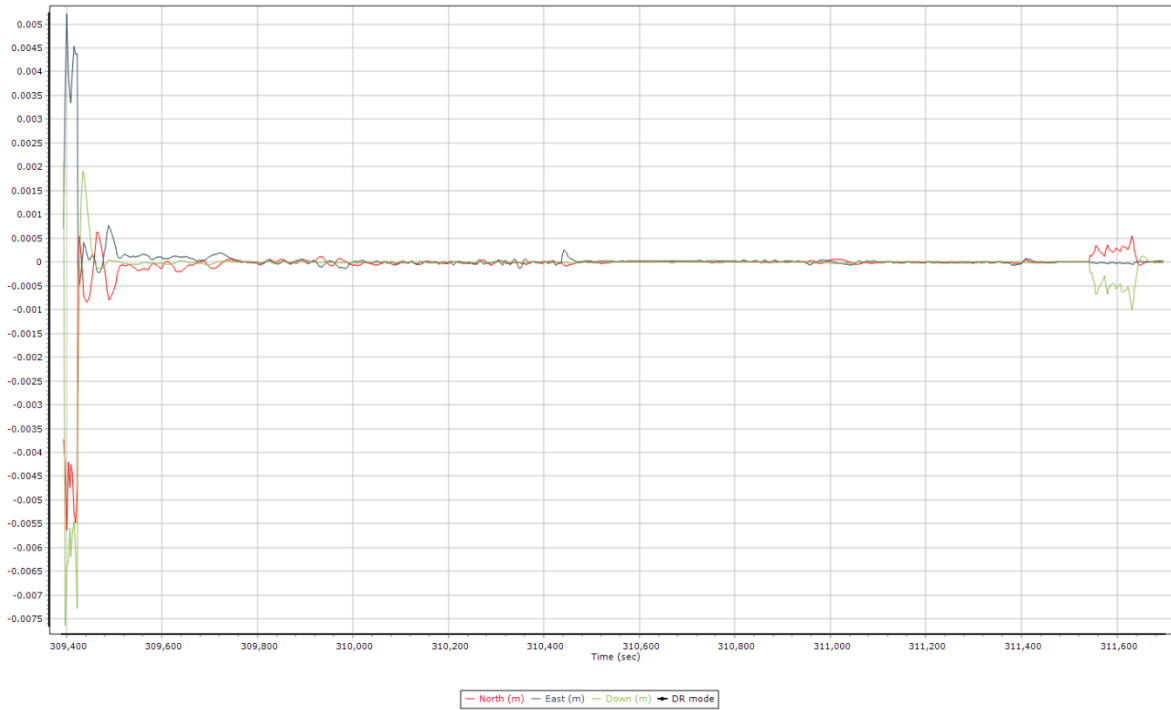
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel

RBV18073A1







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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation

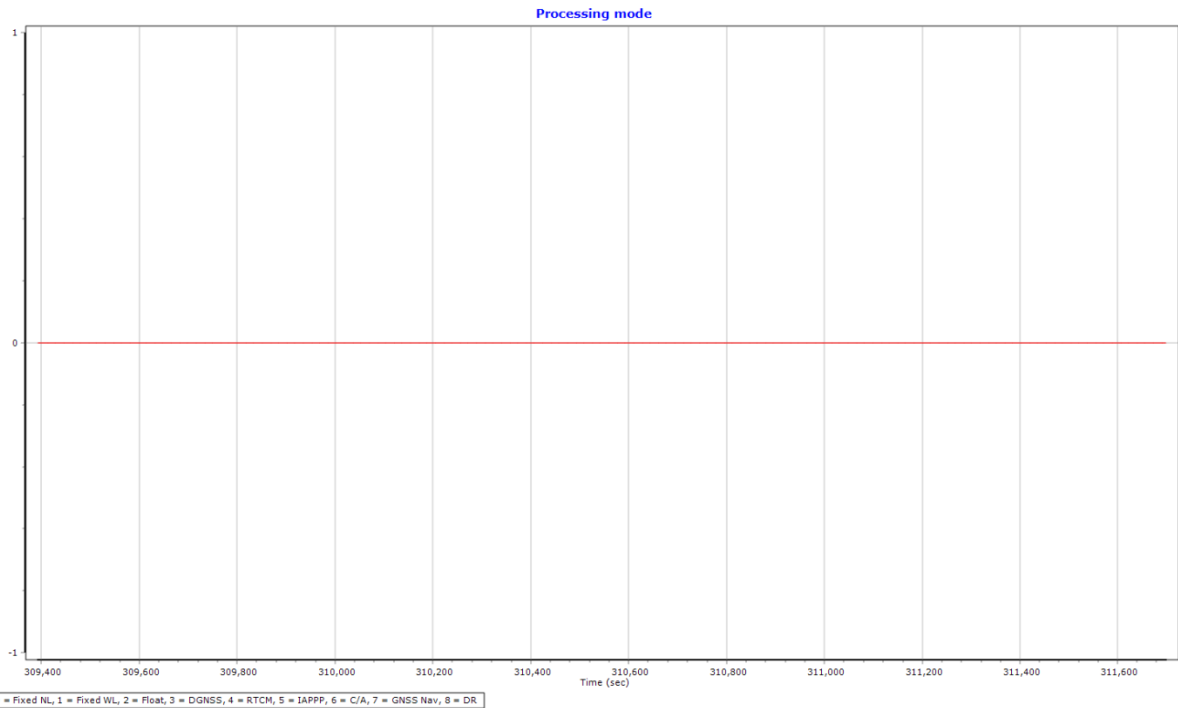
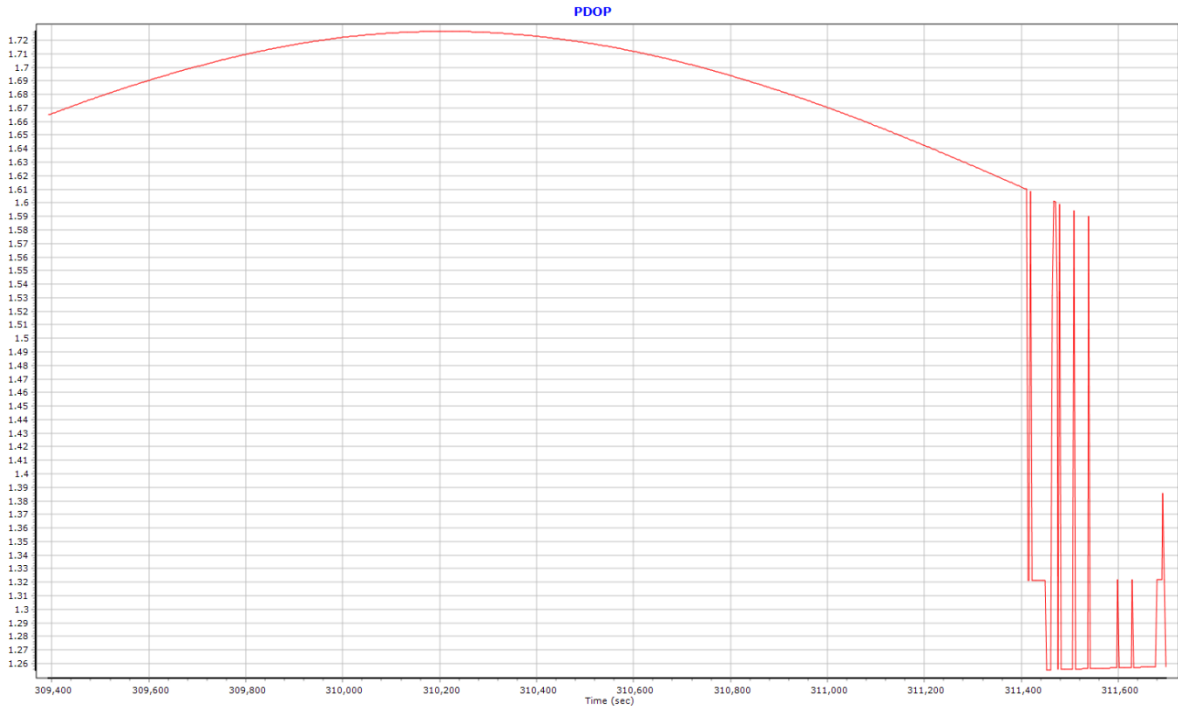
<3cm 10cm 50cm 1m 10m

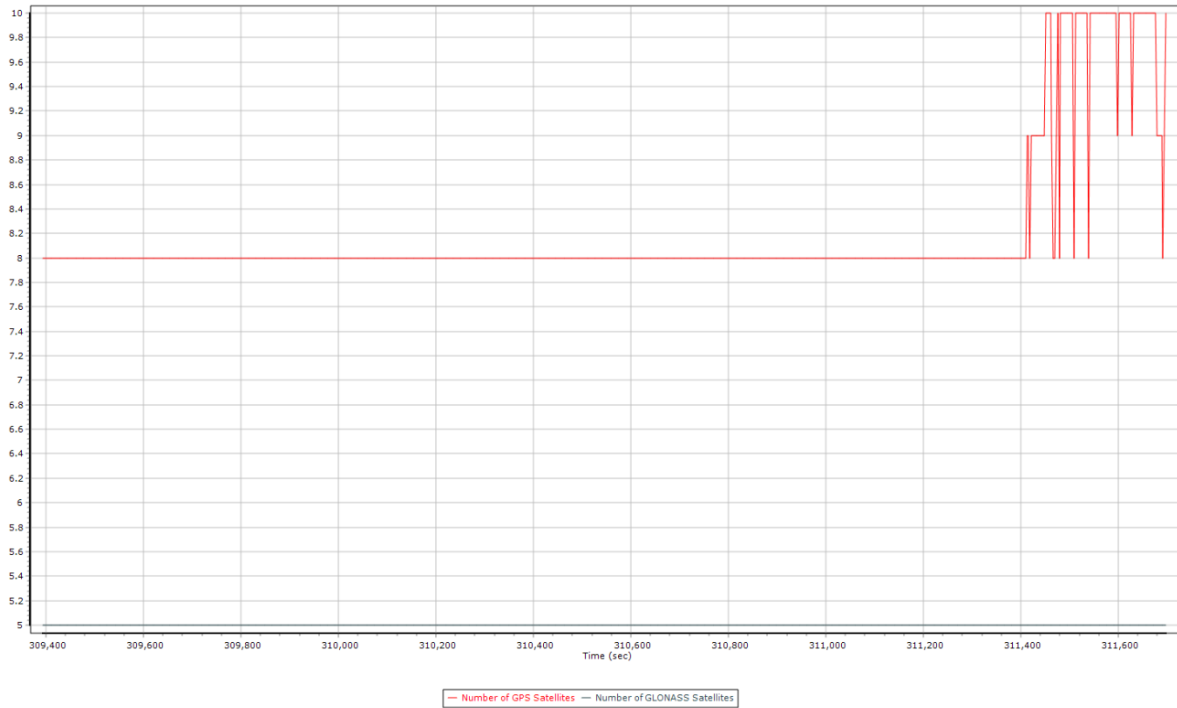
Aircraft to Reference Mounting Angles

X:

Y:

Z:





Project Settings [X]

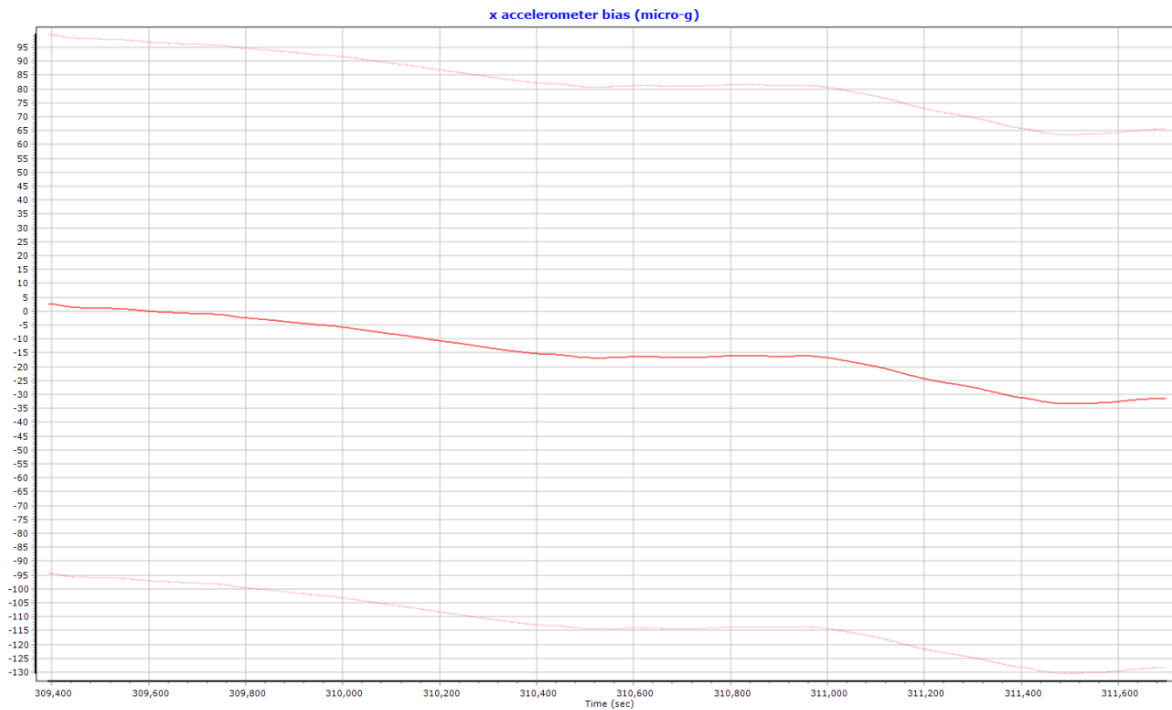
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing**
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

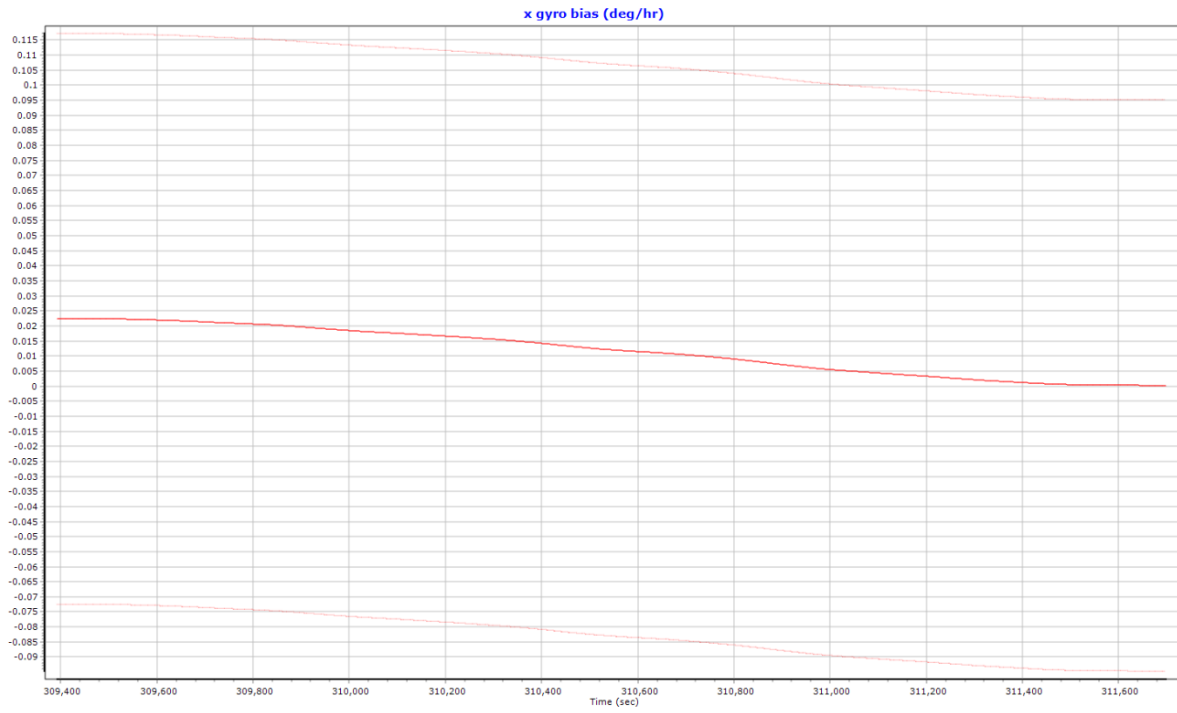
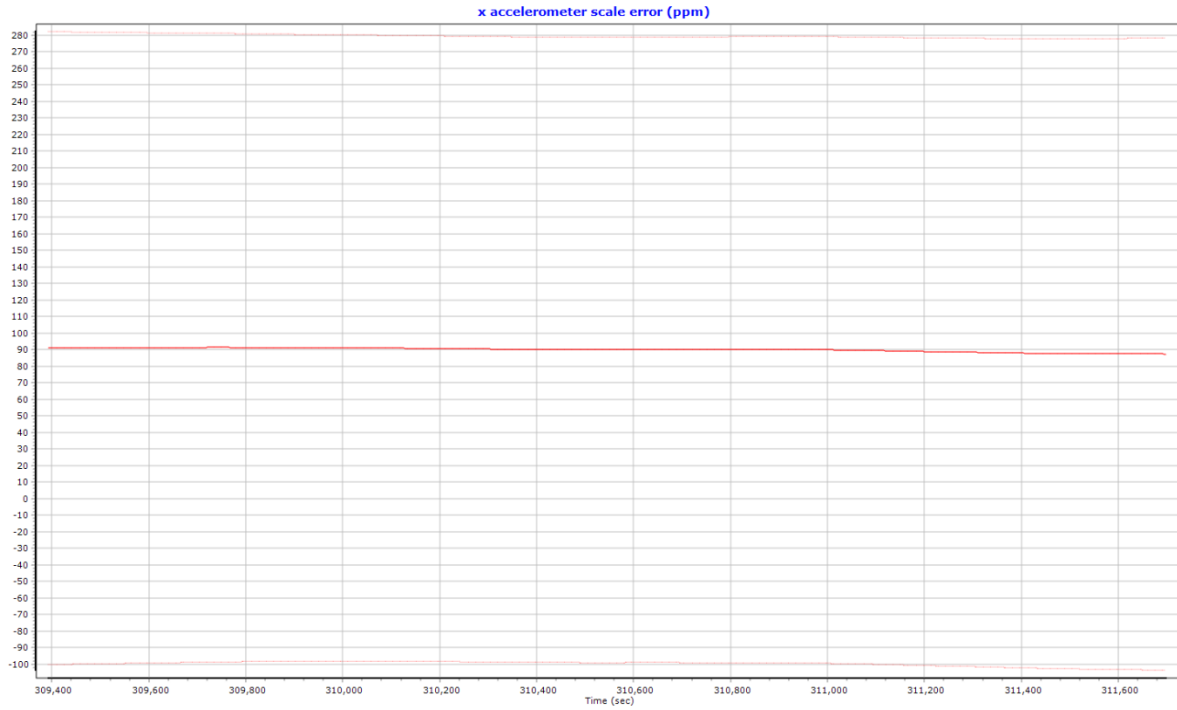
Timing

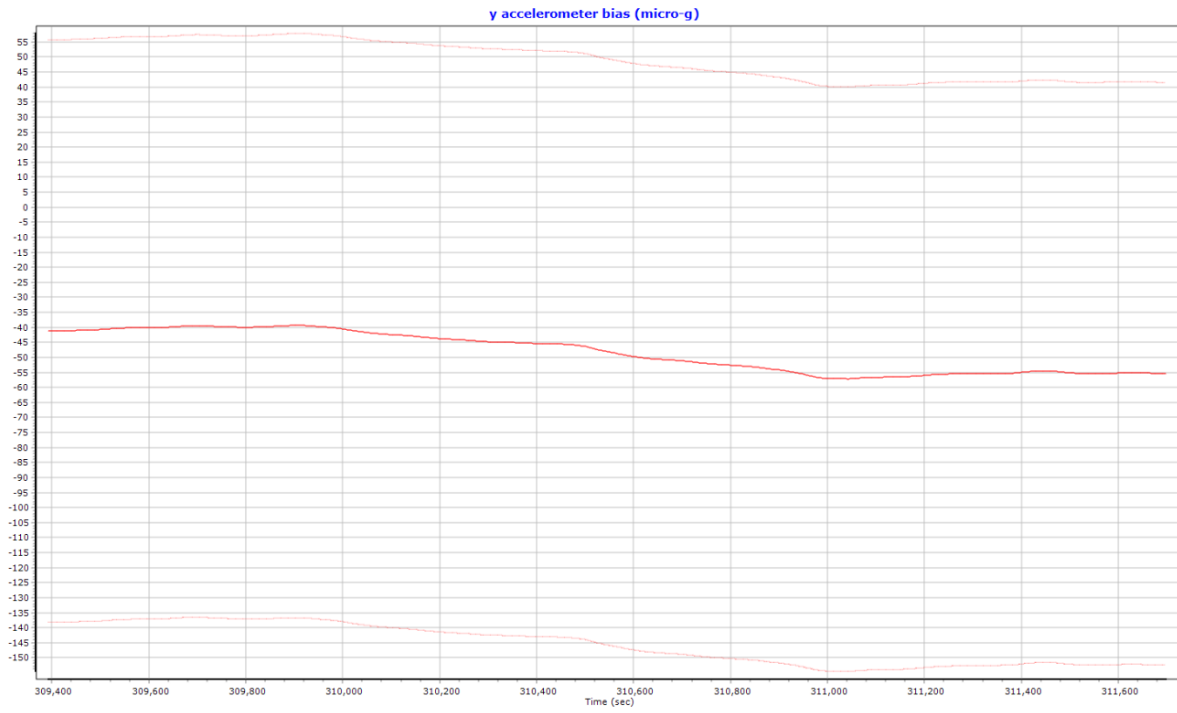
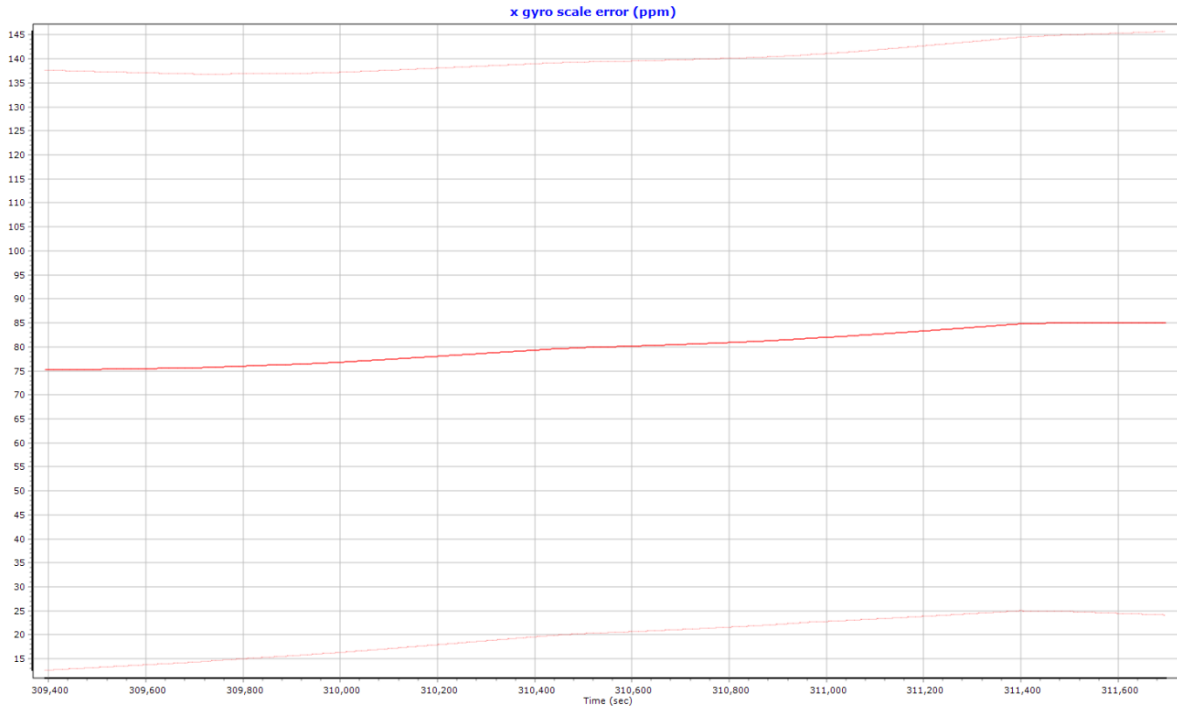
Start: 309390.815
End: 311701.339
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

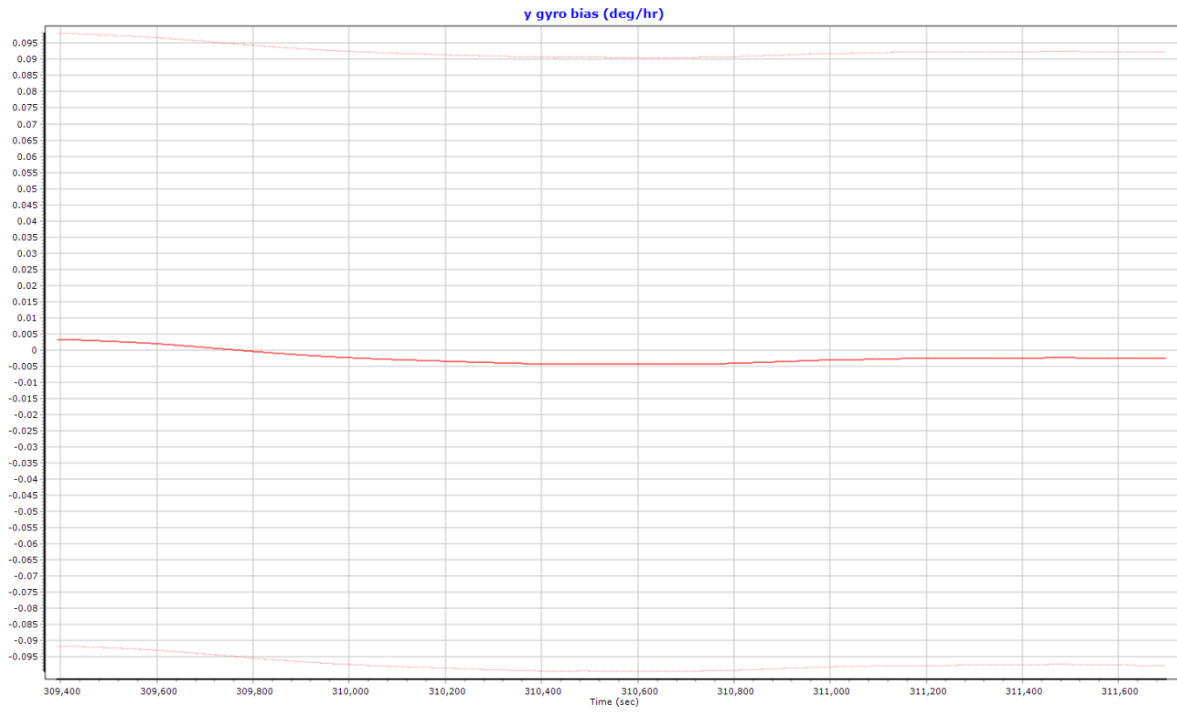
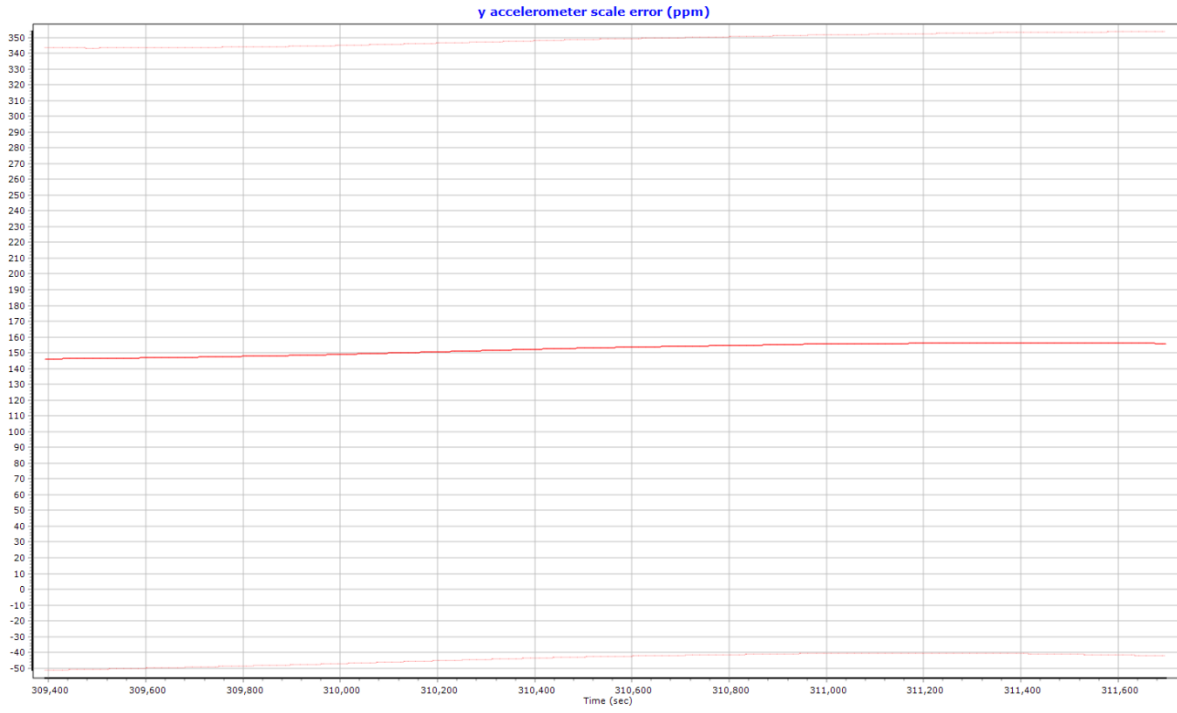
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

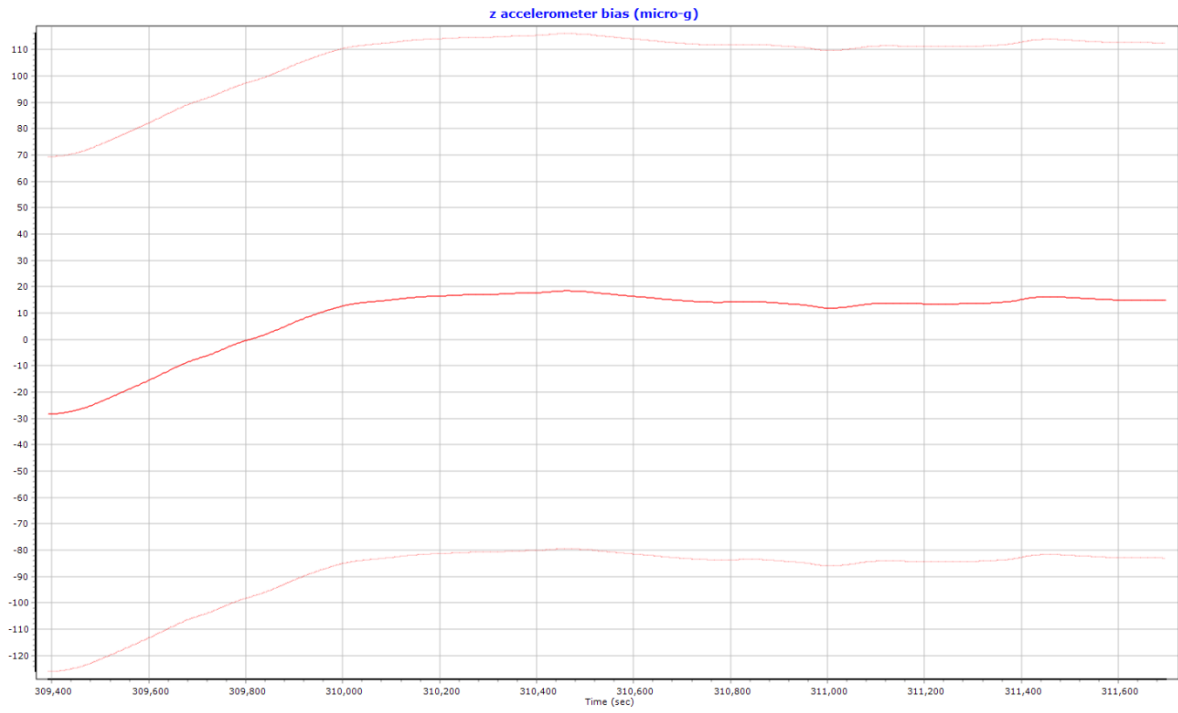
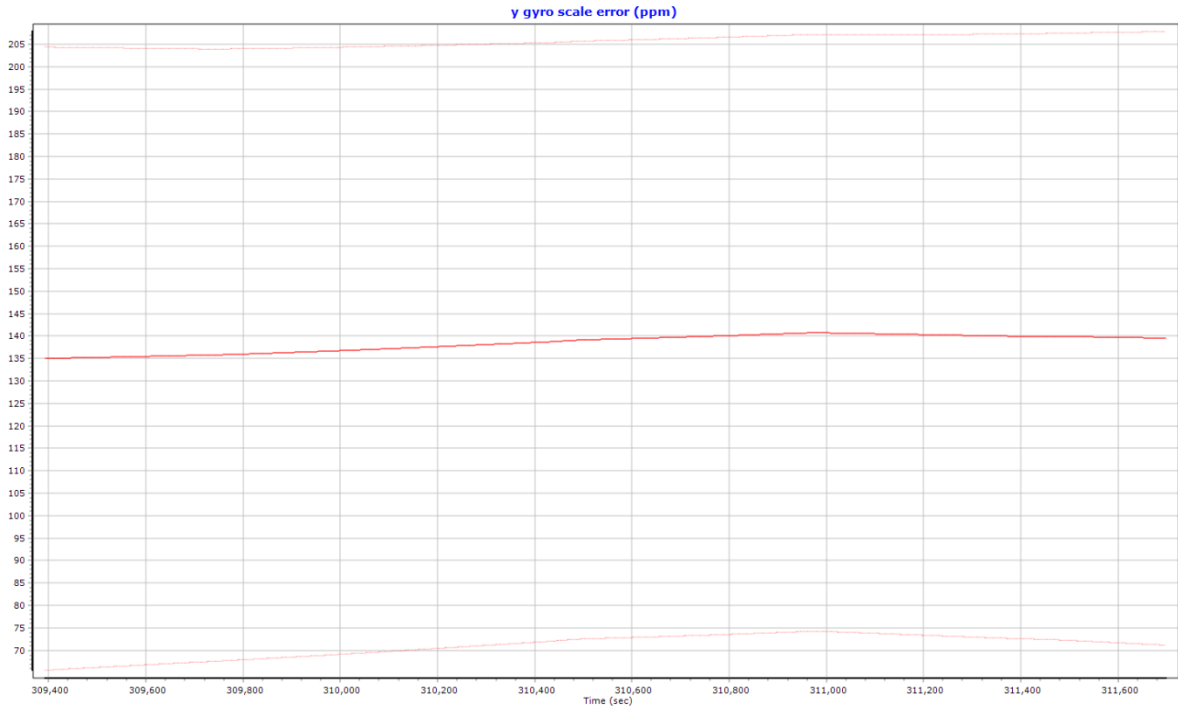
OK Cancel

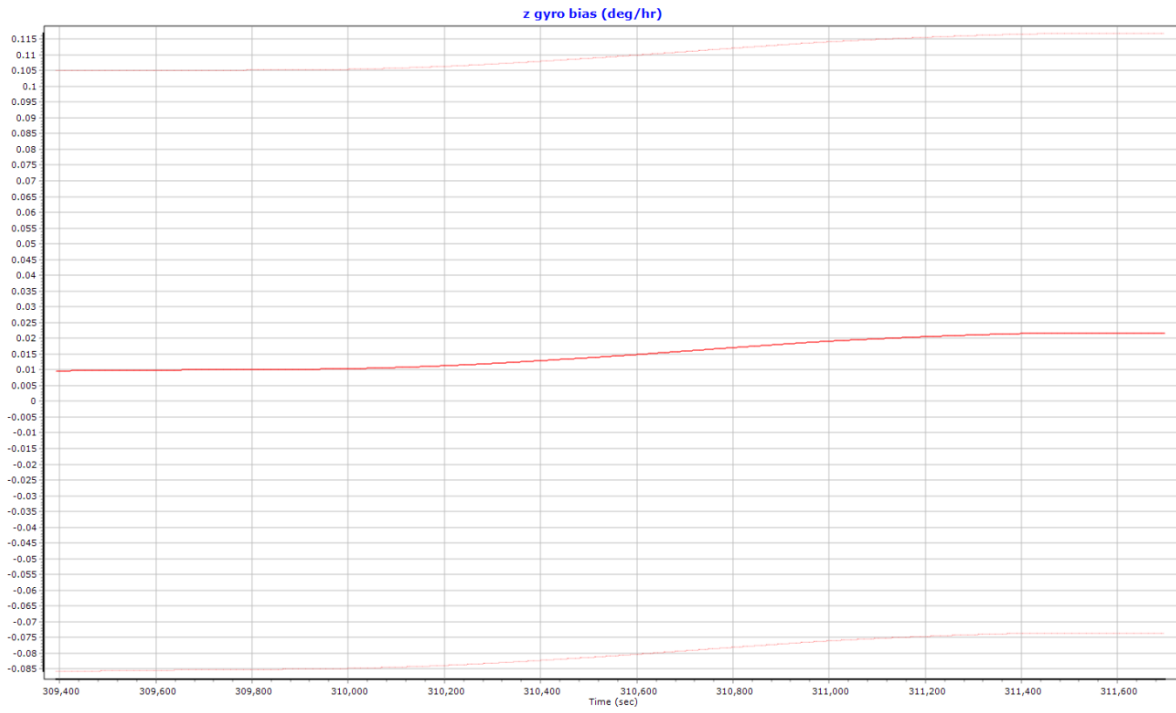
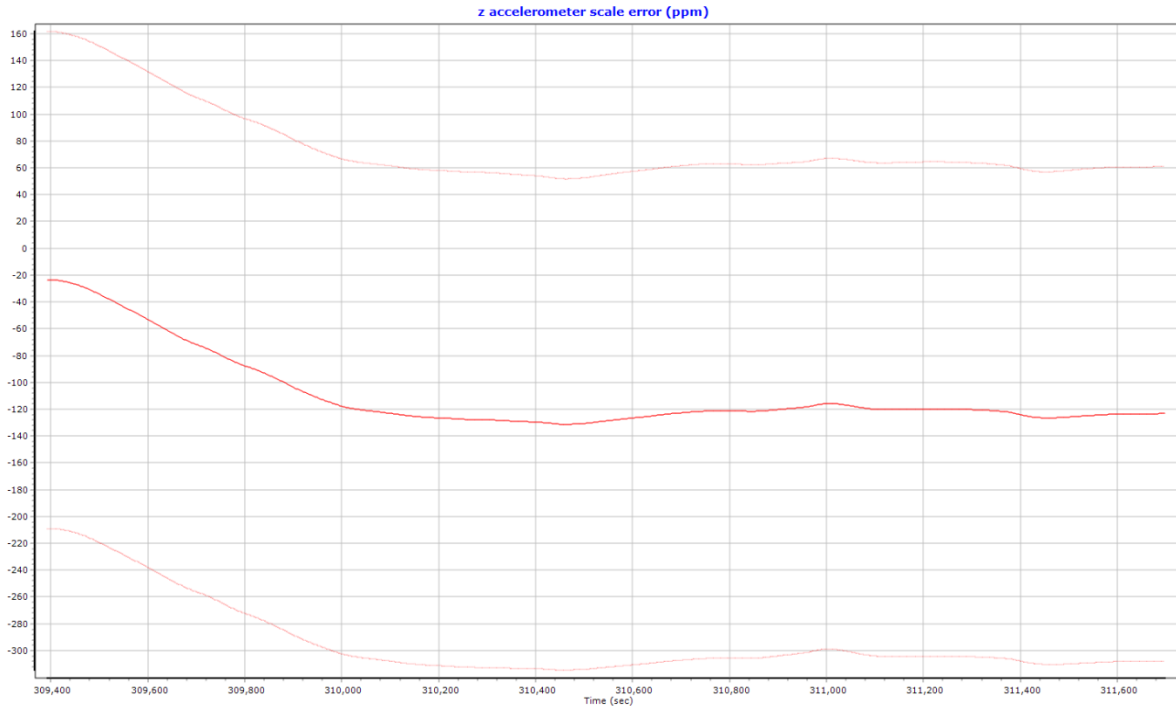


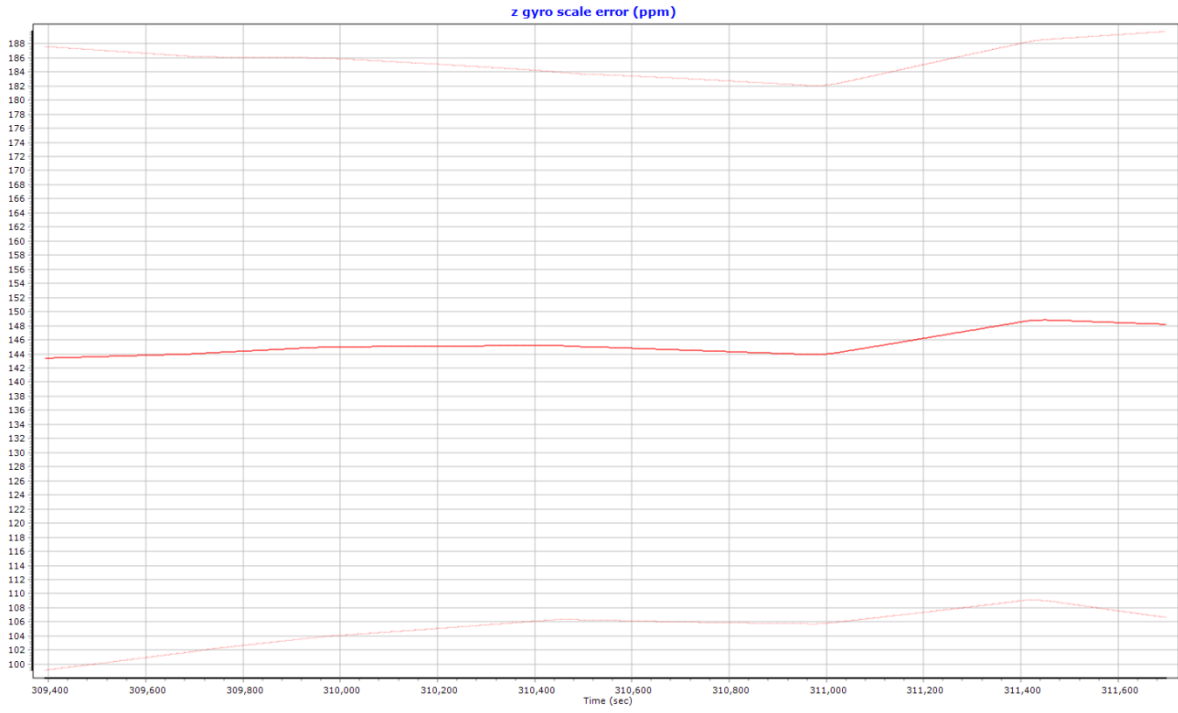




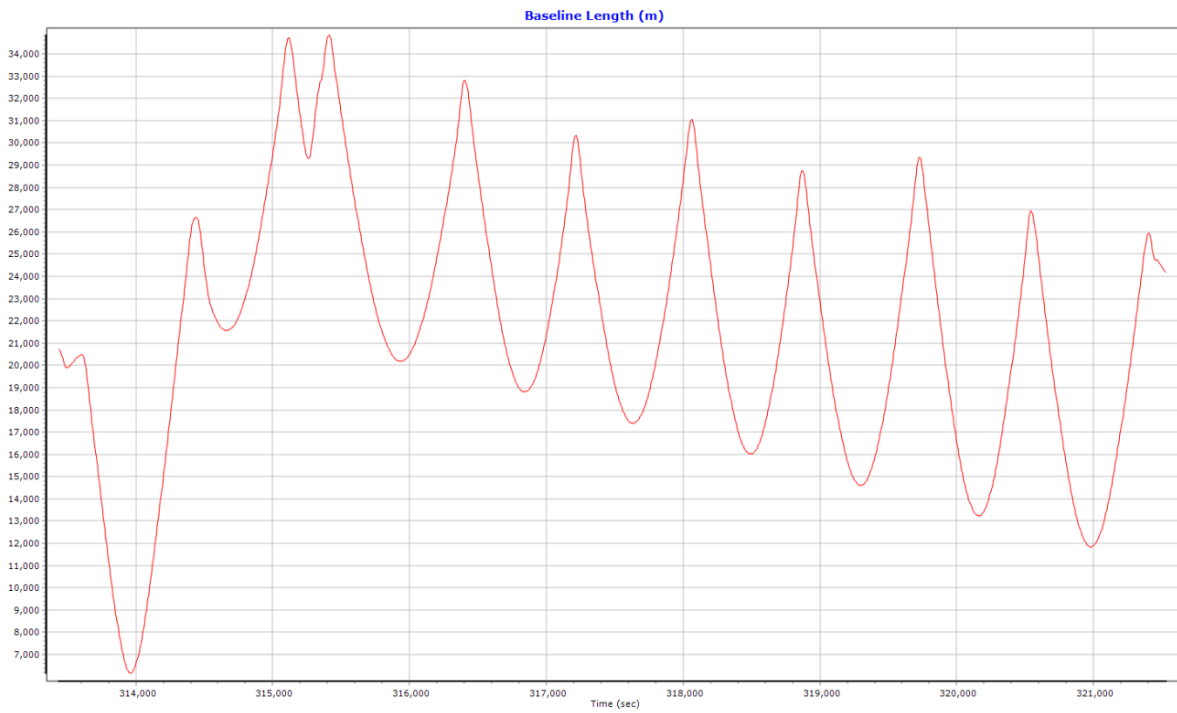
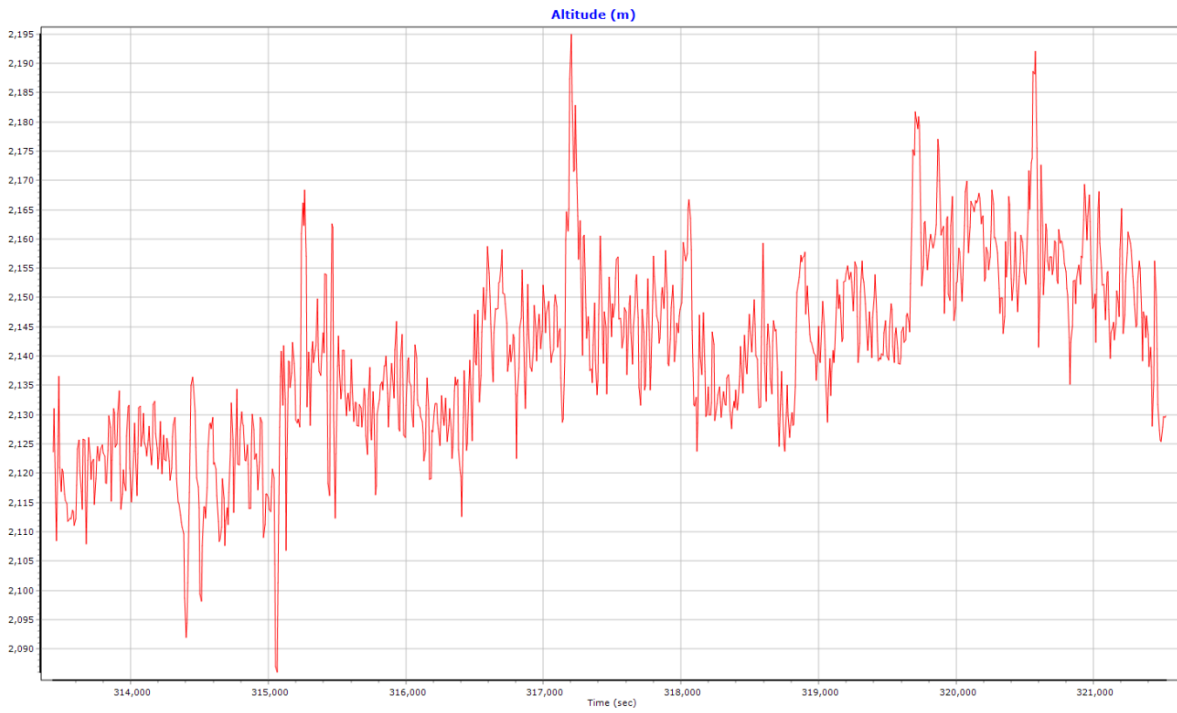


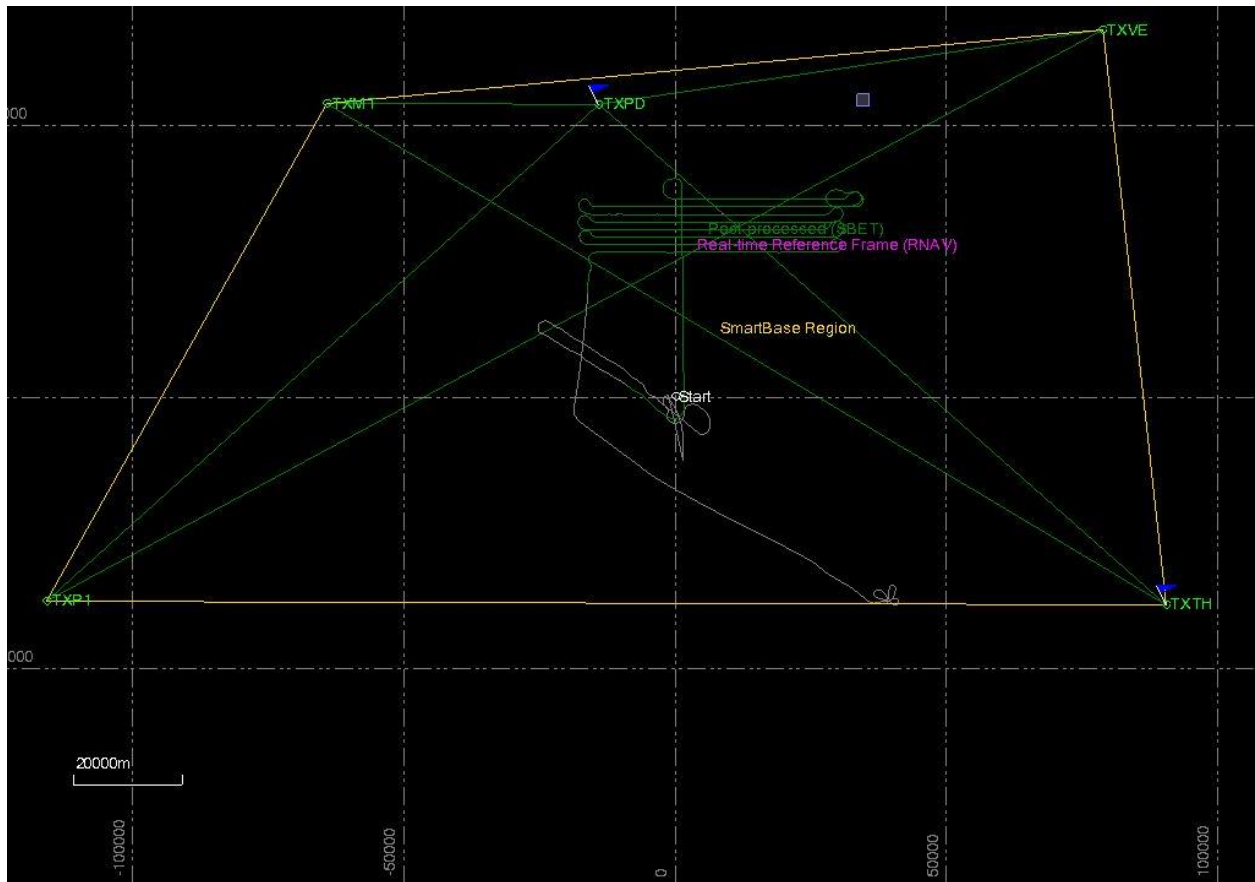






RBV18073A2





Project Settings

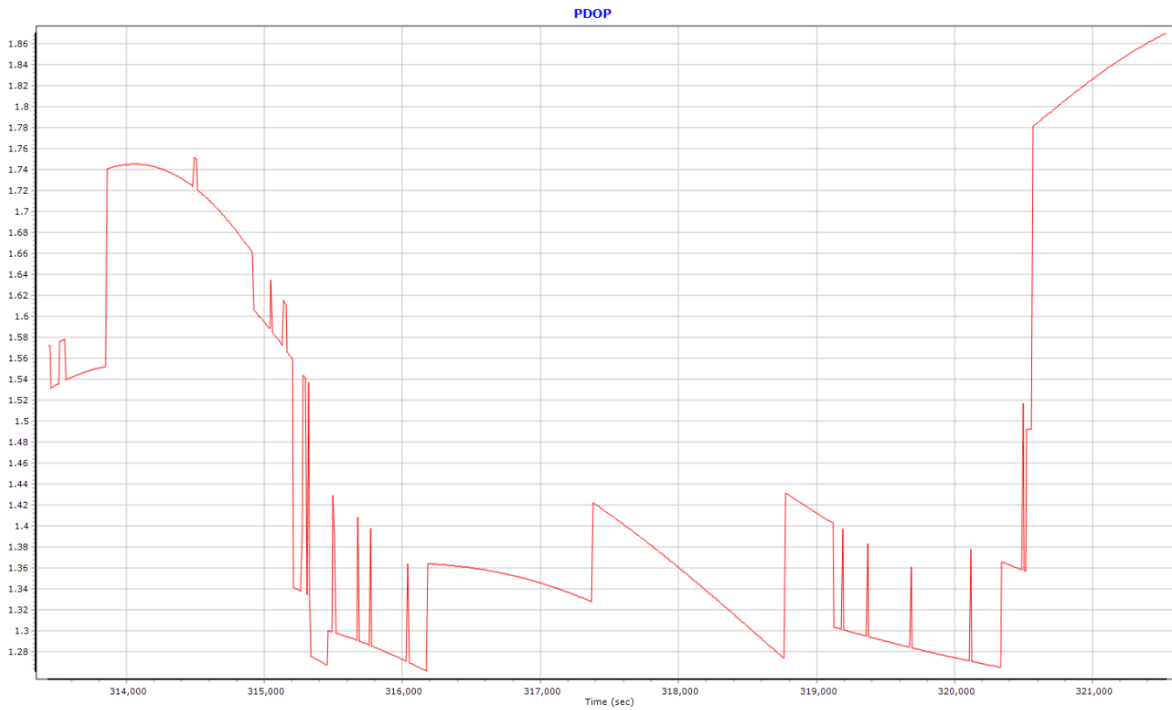
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

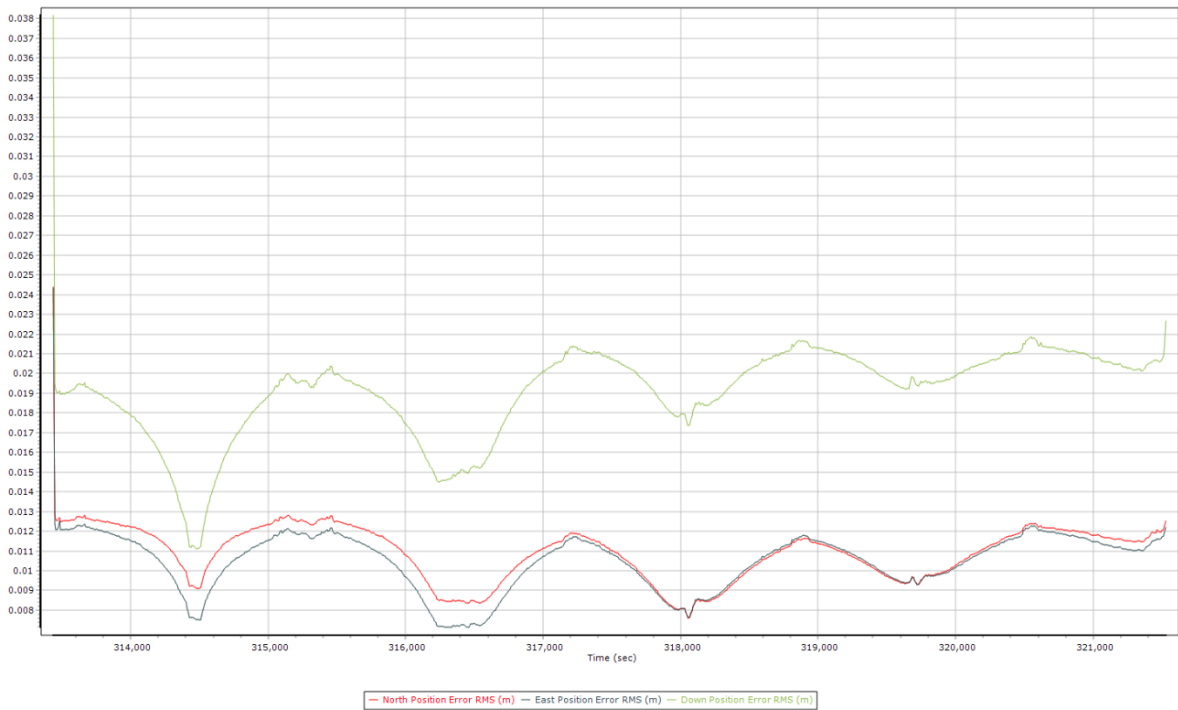
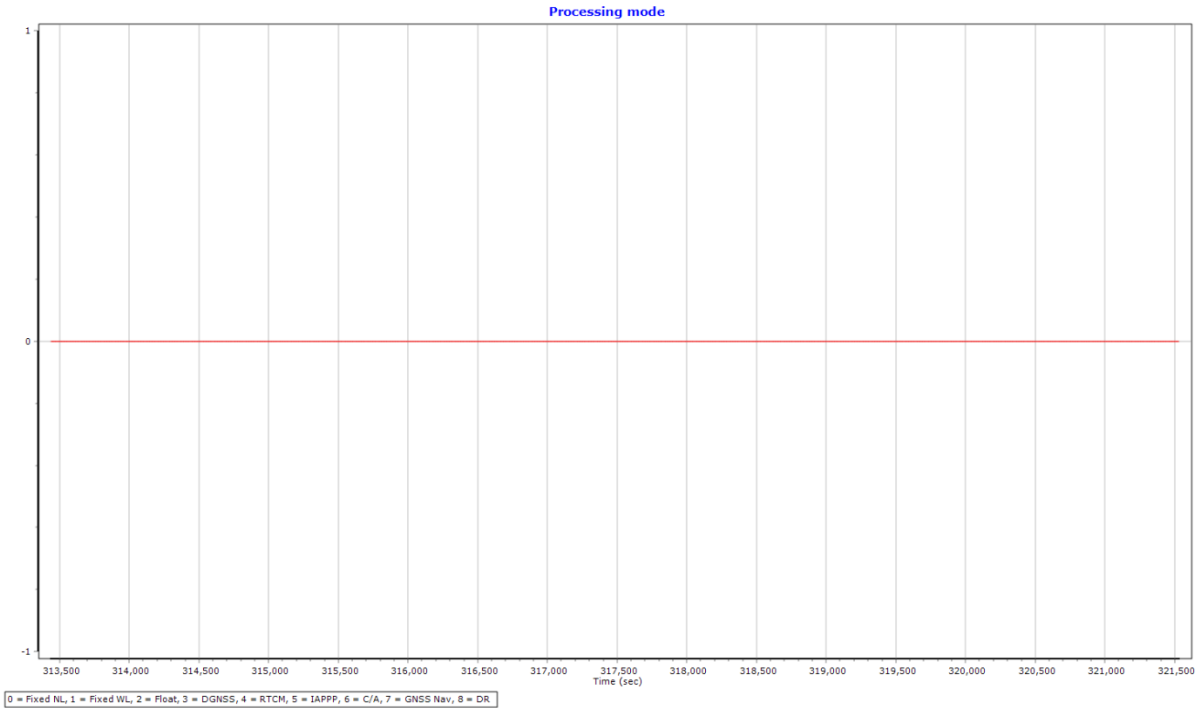
Reference to IMU Lever Arm	Reference to IMU Mounting Angles
X: -0.034 m	X: 0.000 deg
Y: -0.010 m	Y: 0.000 deg
Z: -0.352 m	Z: 0.000 deg

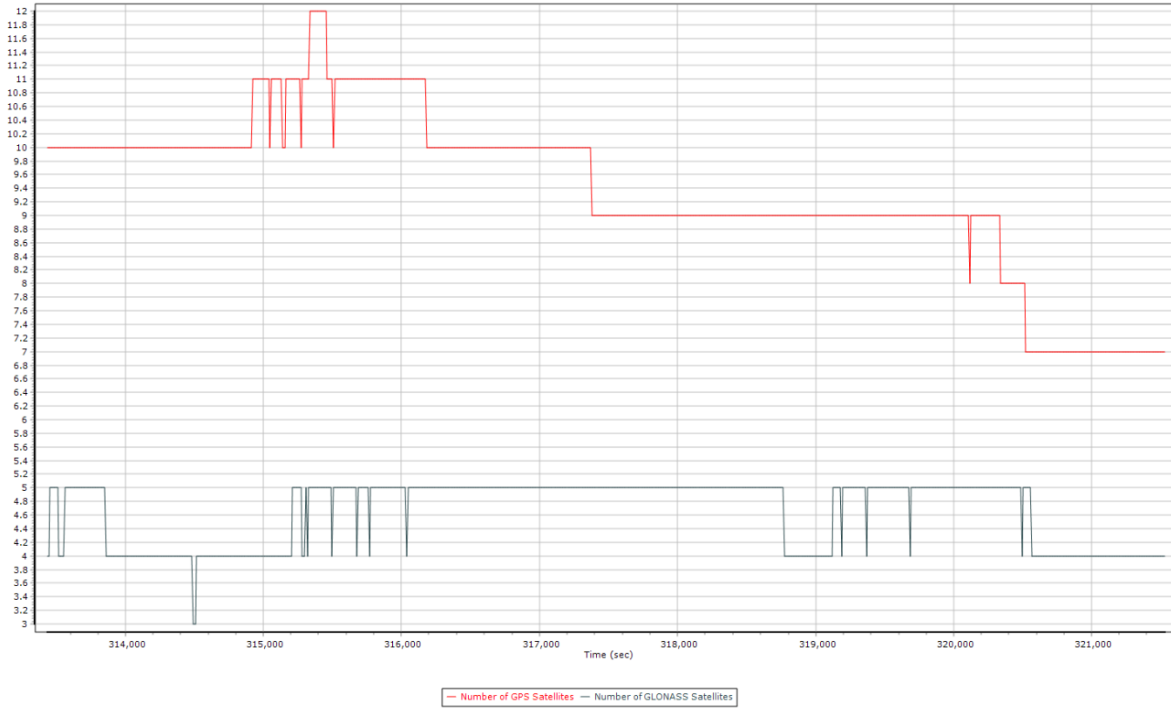
Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.065 m	X: 0.000 deg
Y: 0.014 m	Y: 0.000 deg
Z: -1.021 m	Z: 0.000 deg

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:

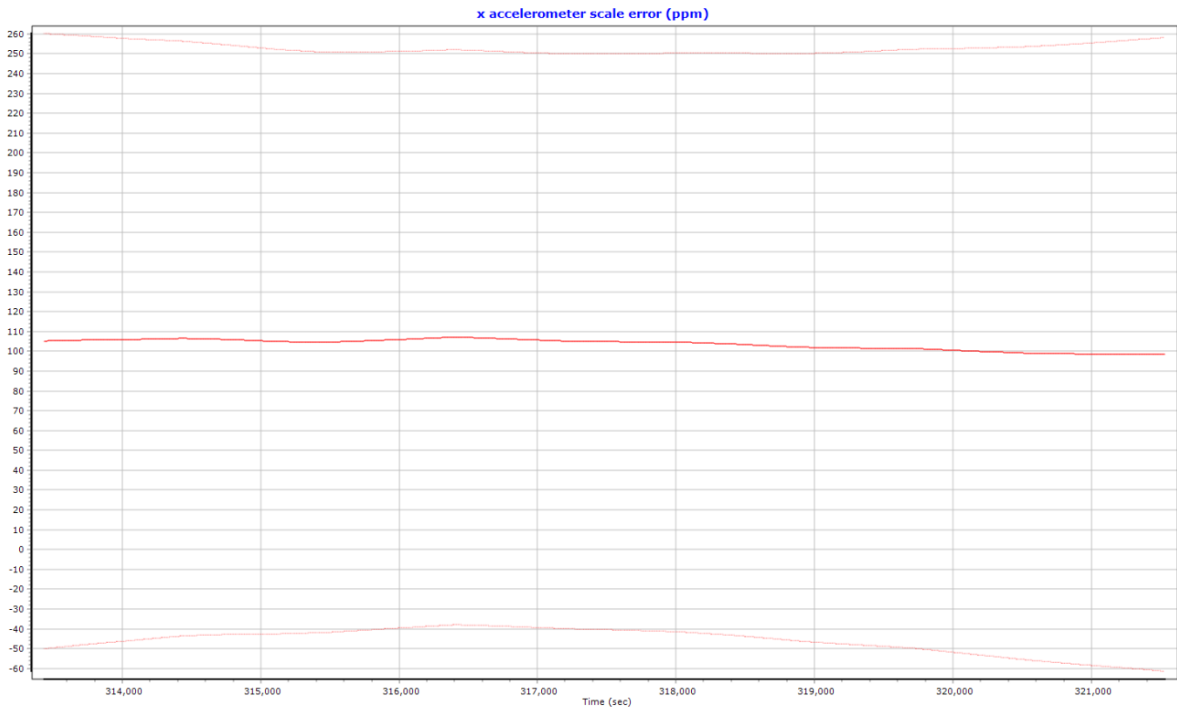
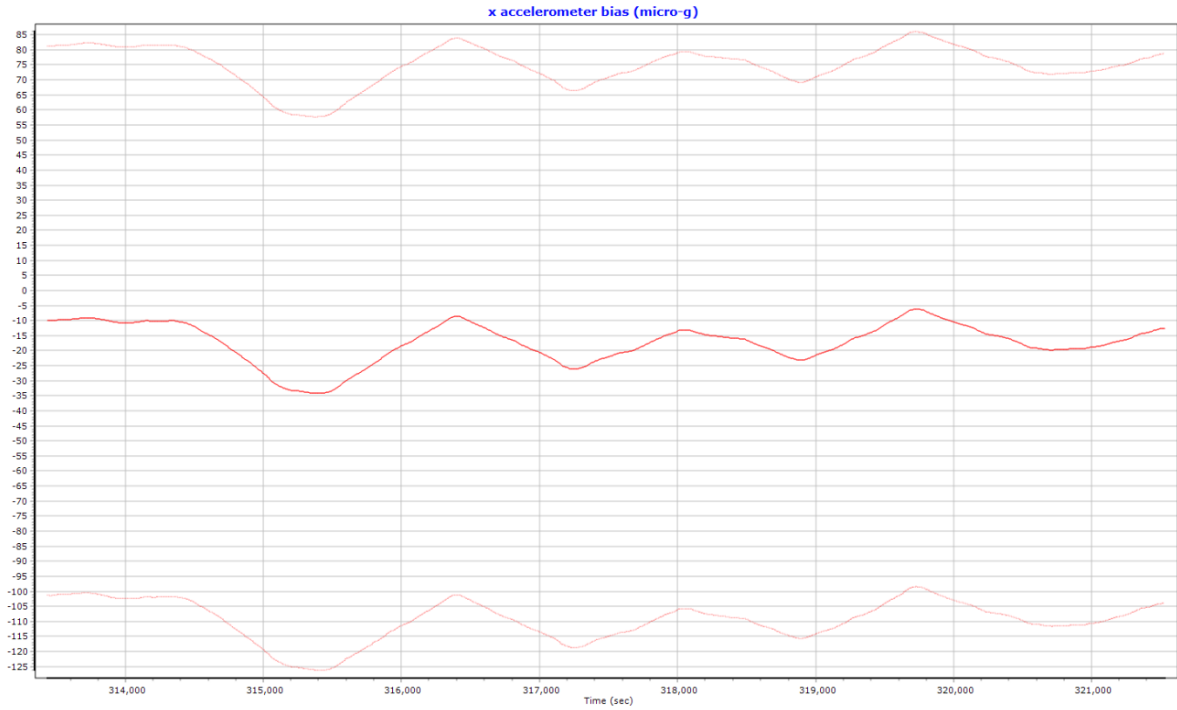
End:

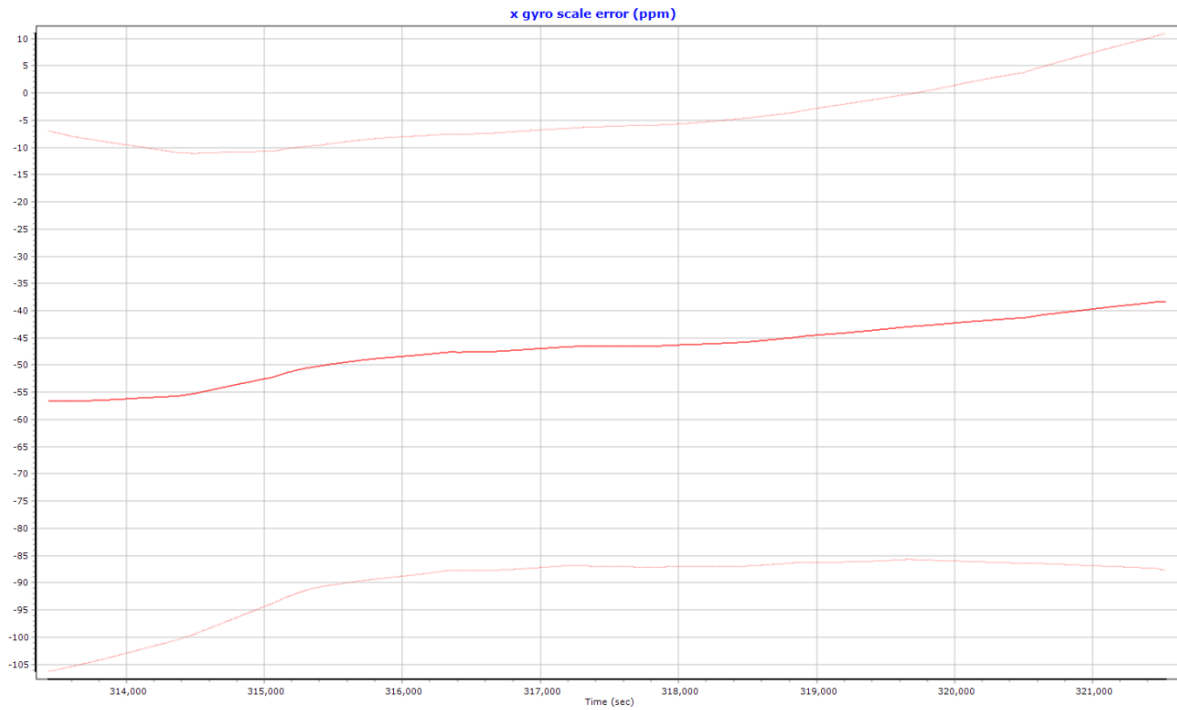
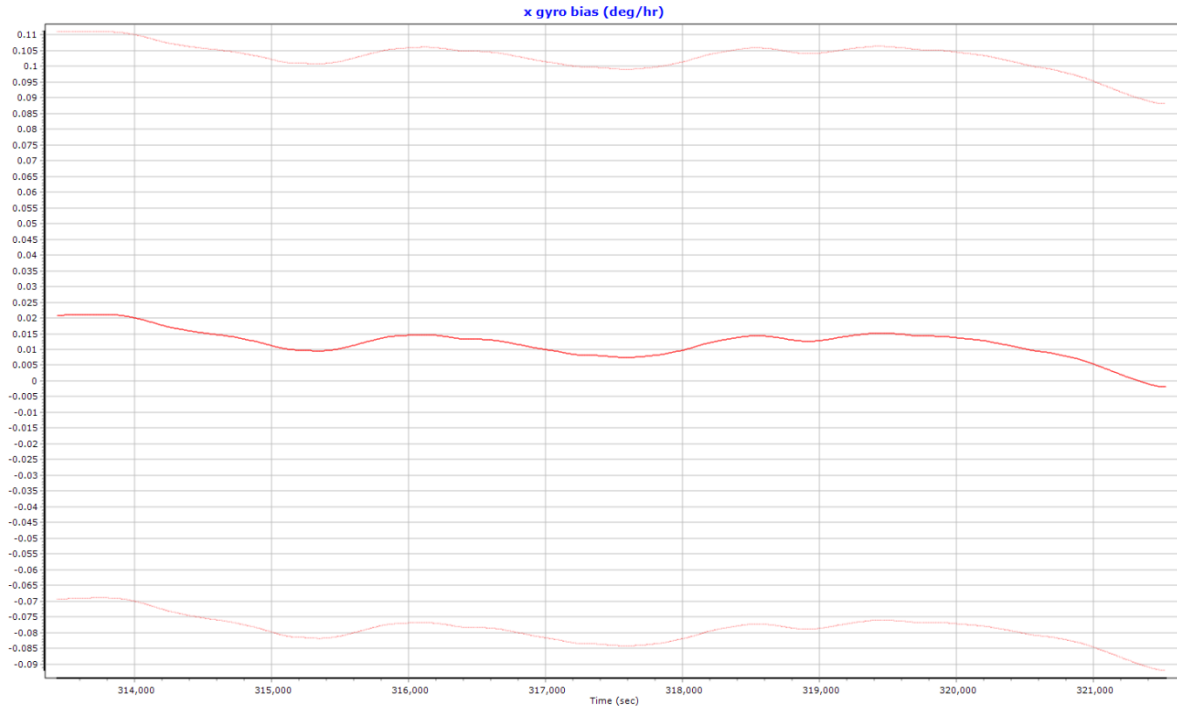
Entire time interval

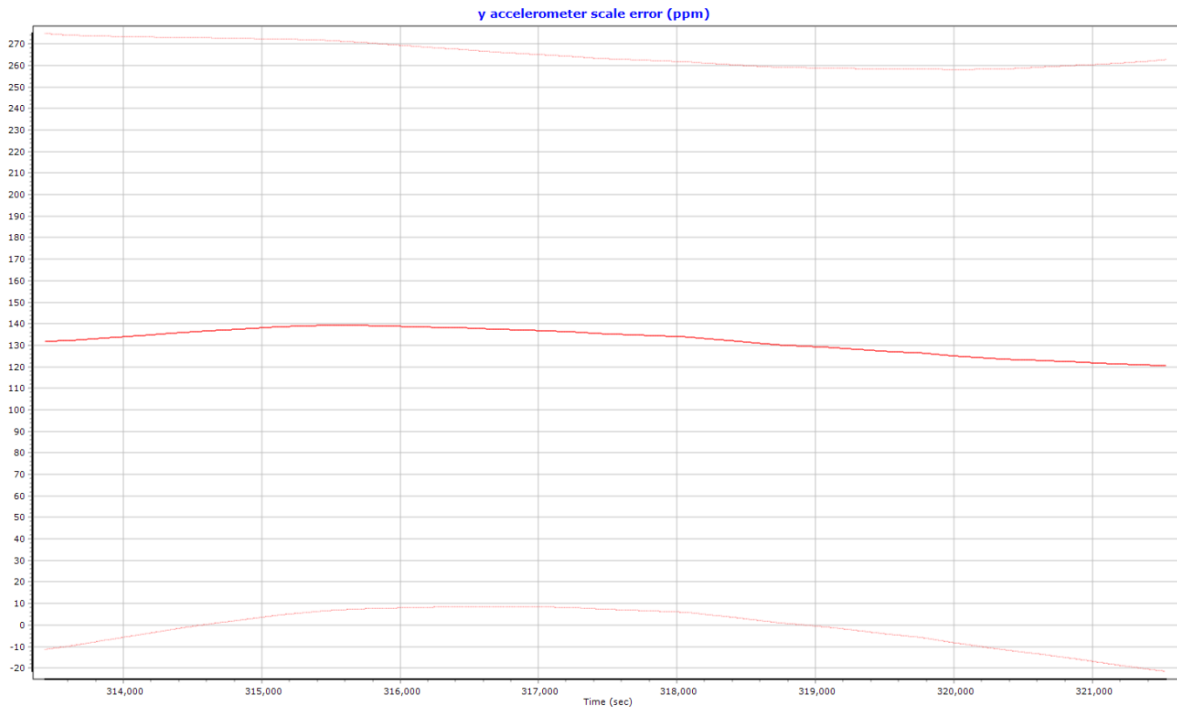
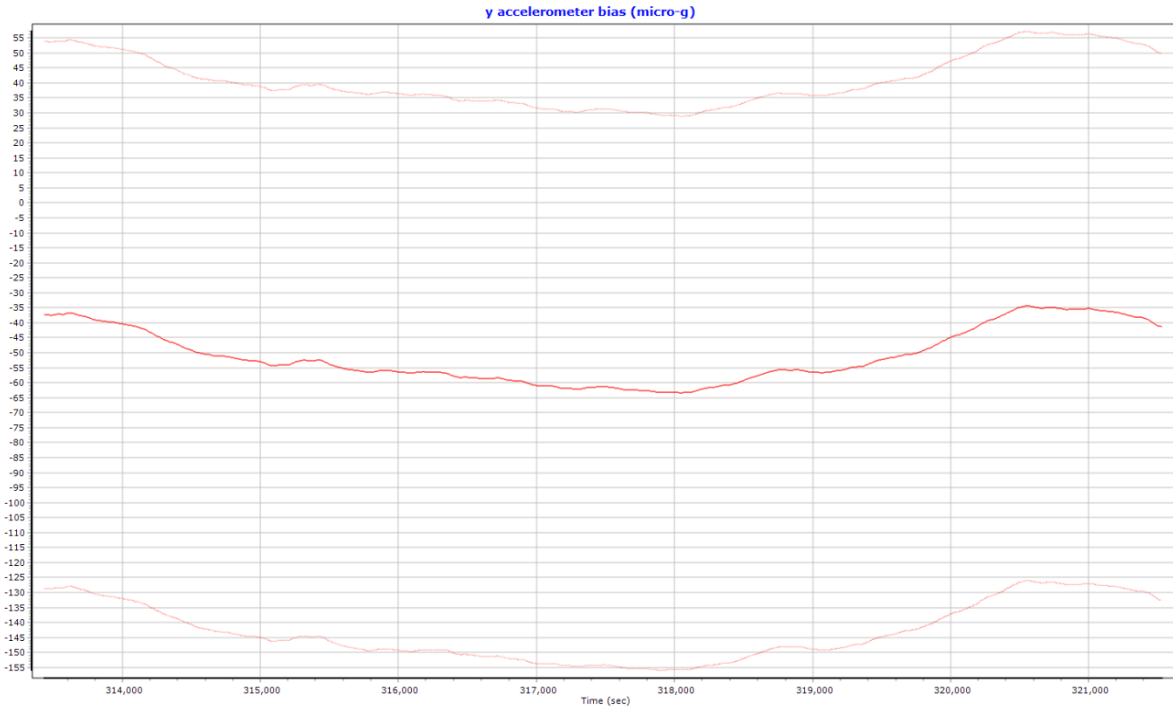
Seconds of start week

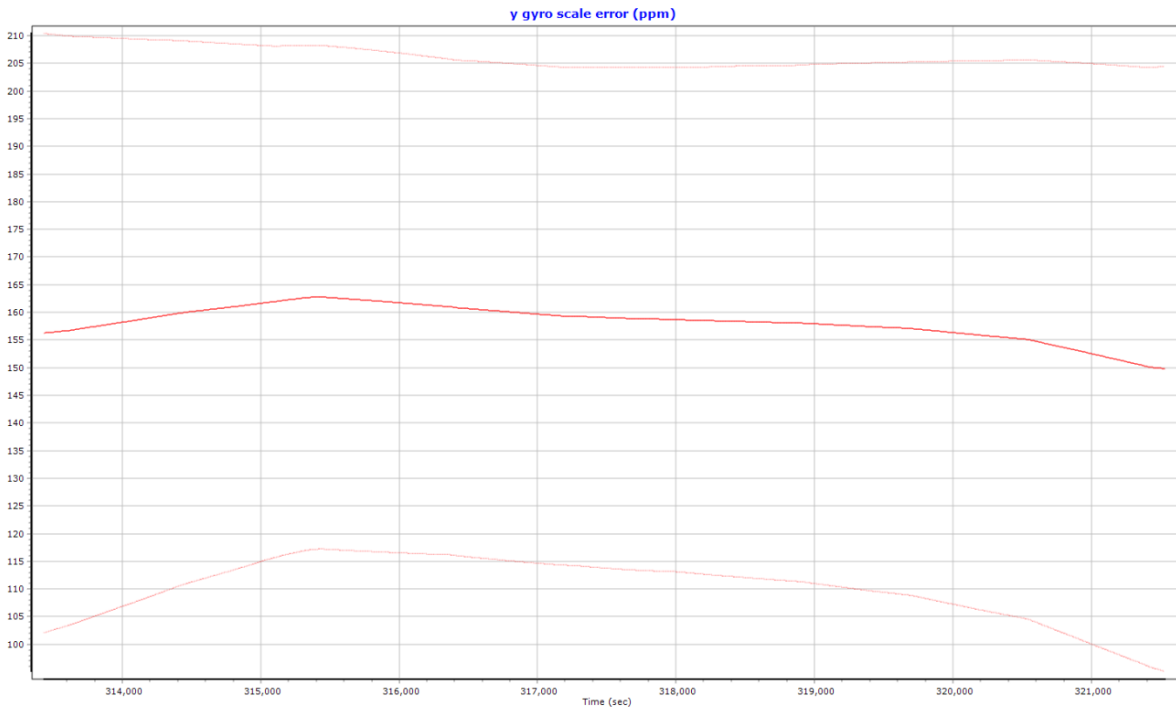
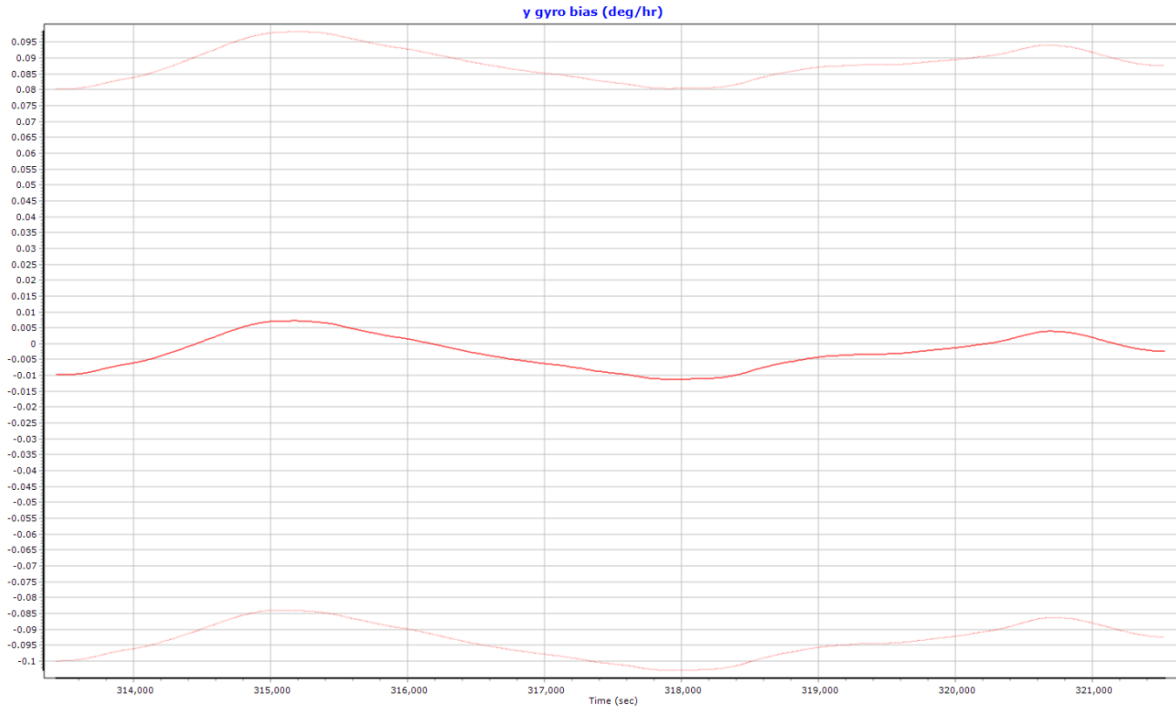
UTC Offset:

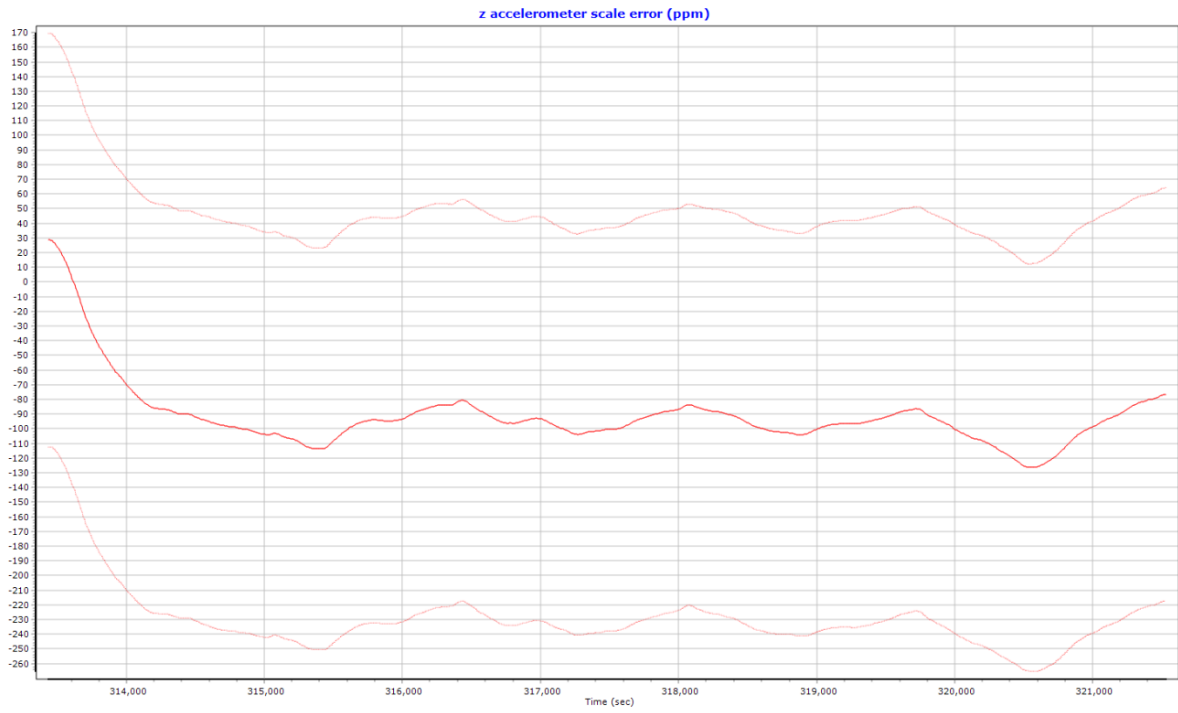
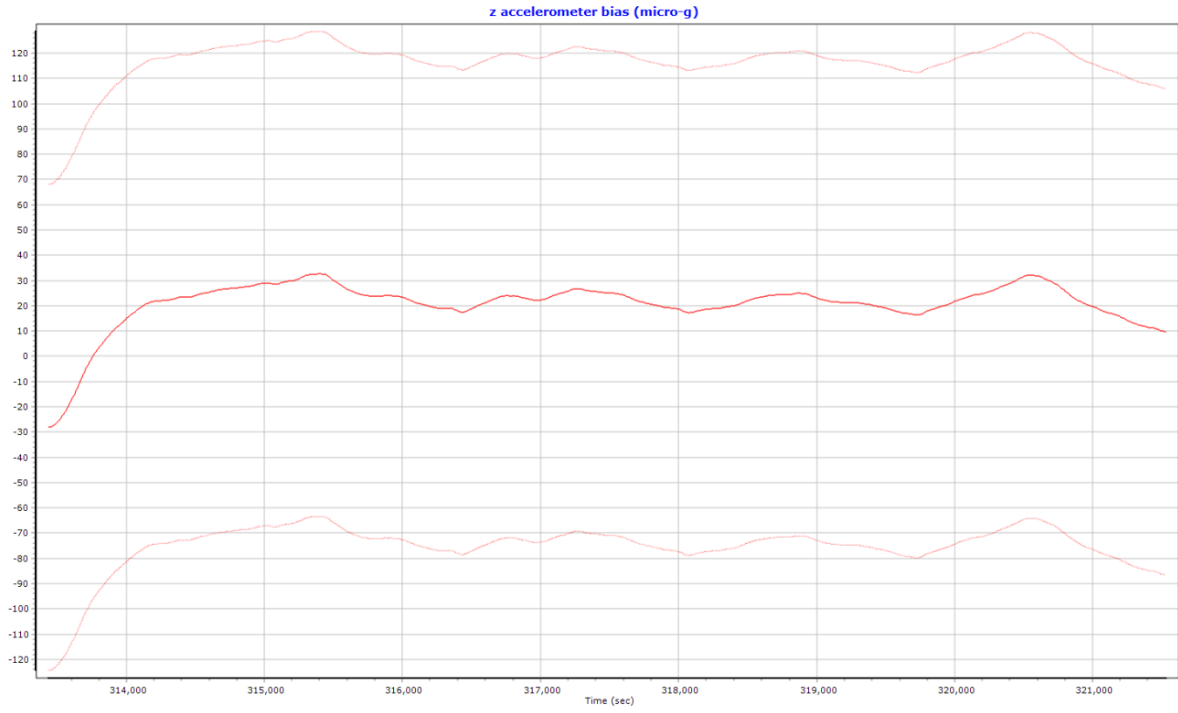
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

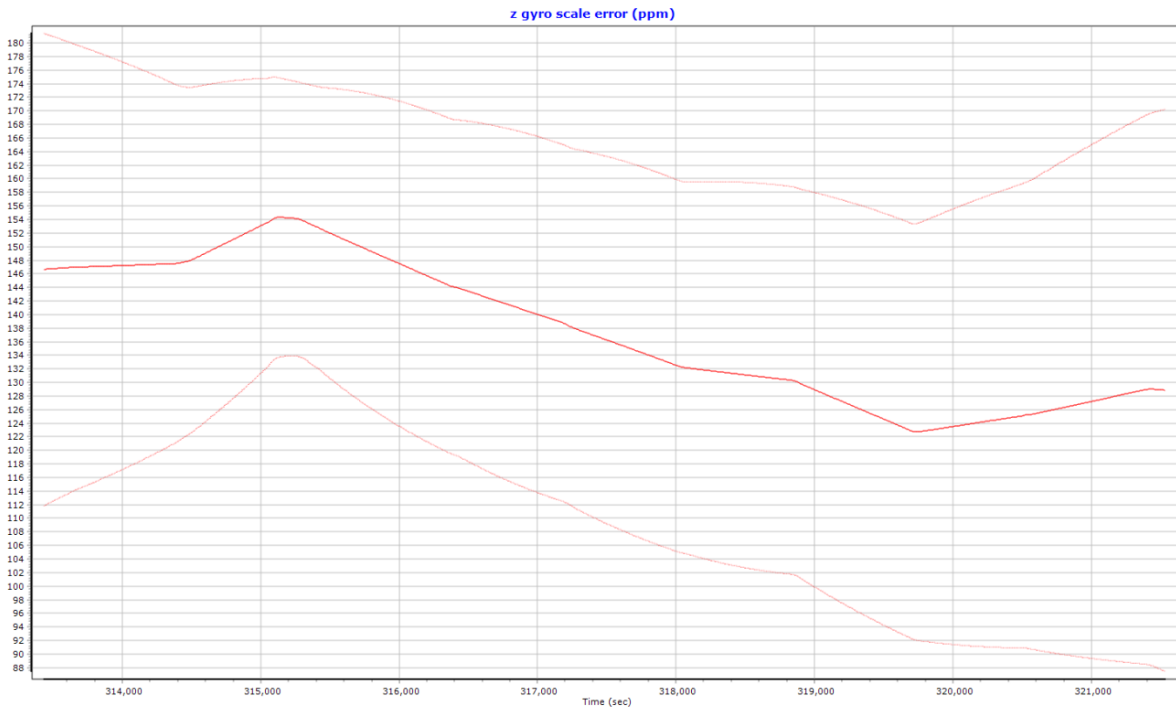
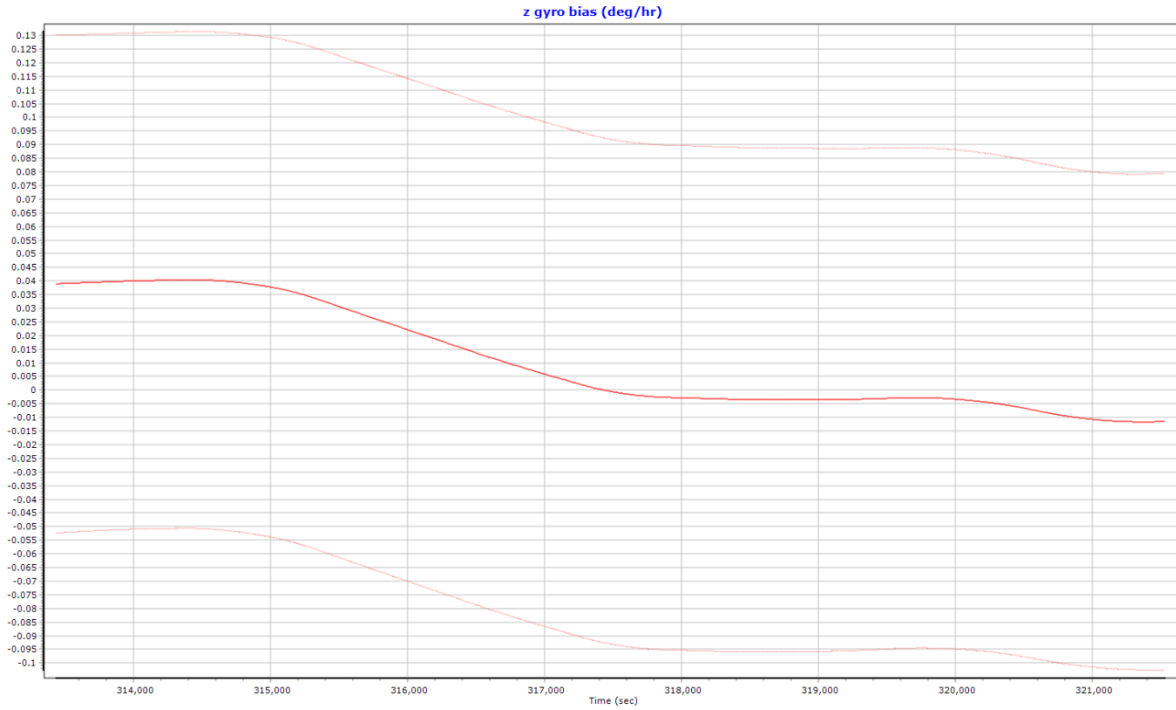




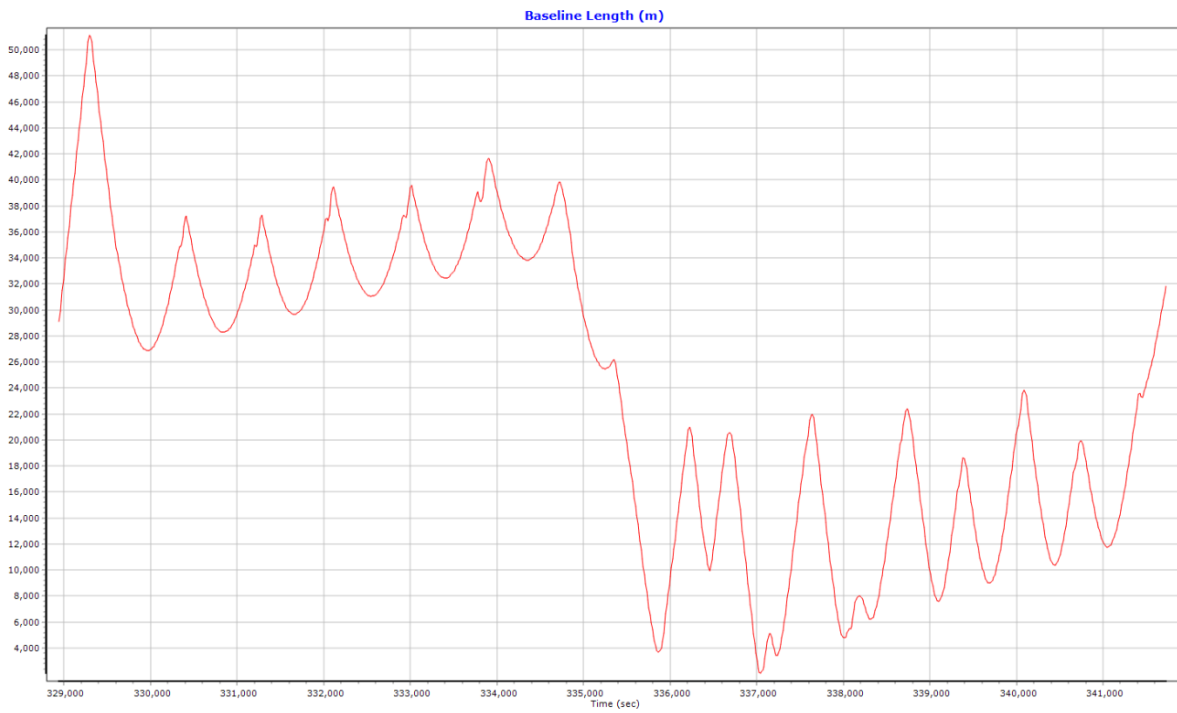
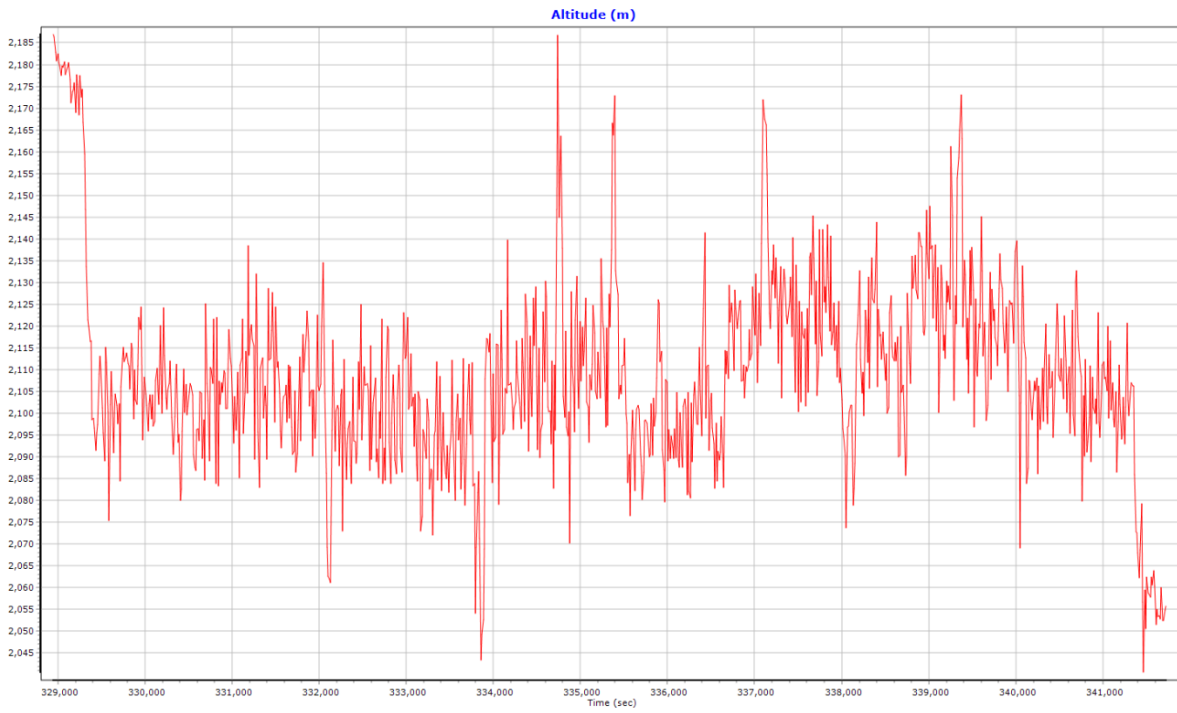


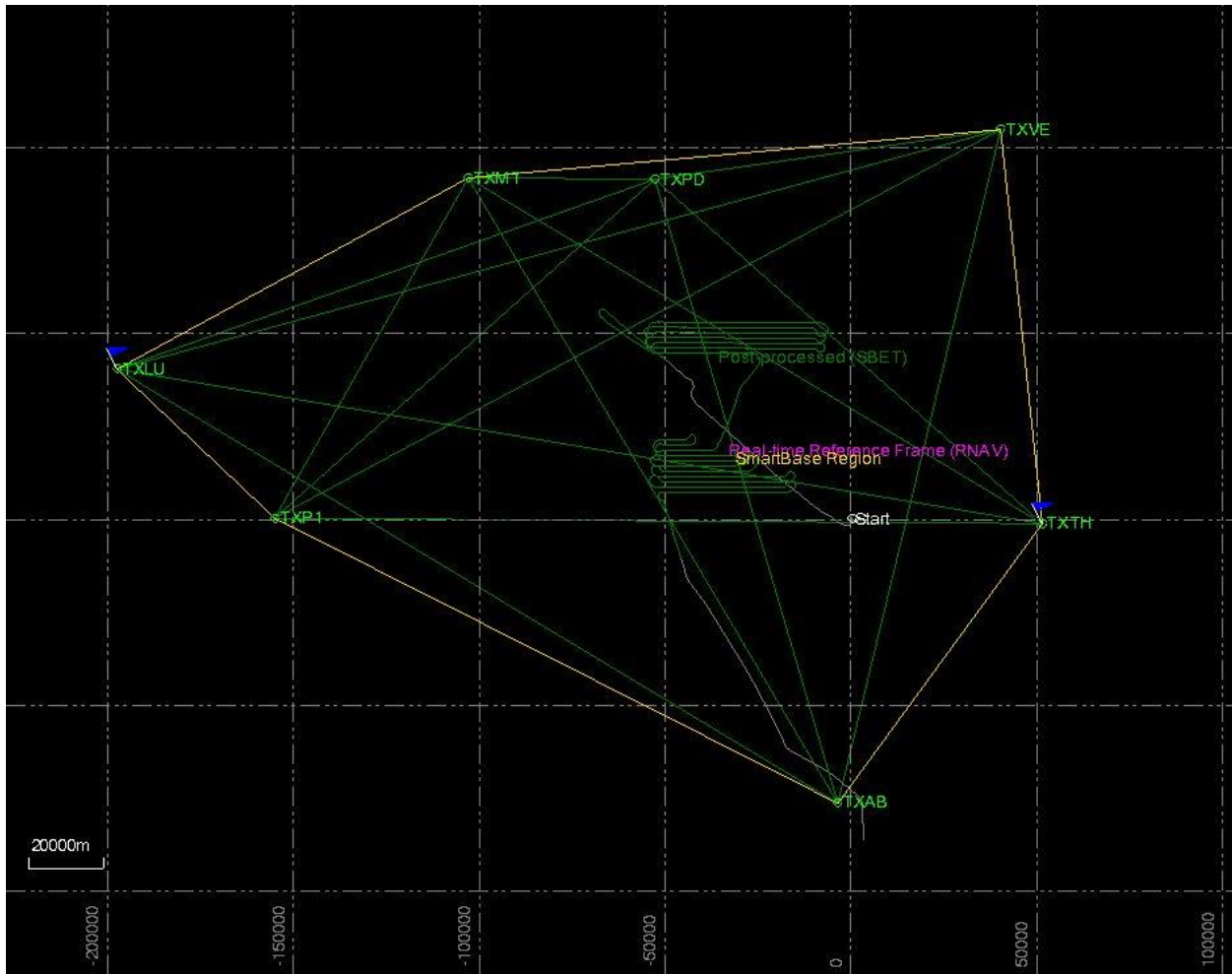






RBV18073B







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

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:

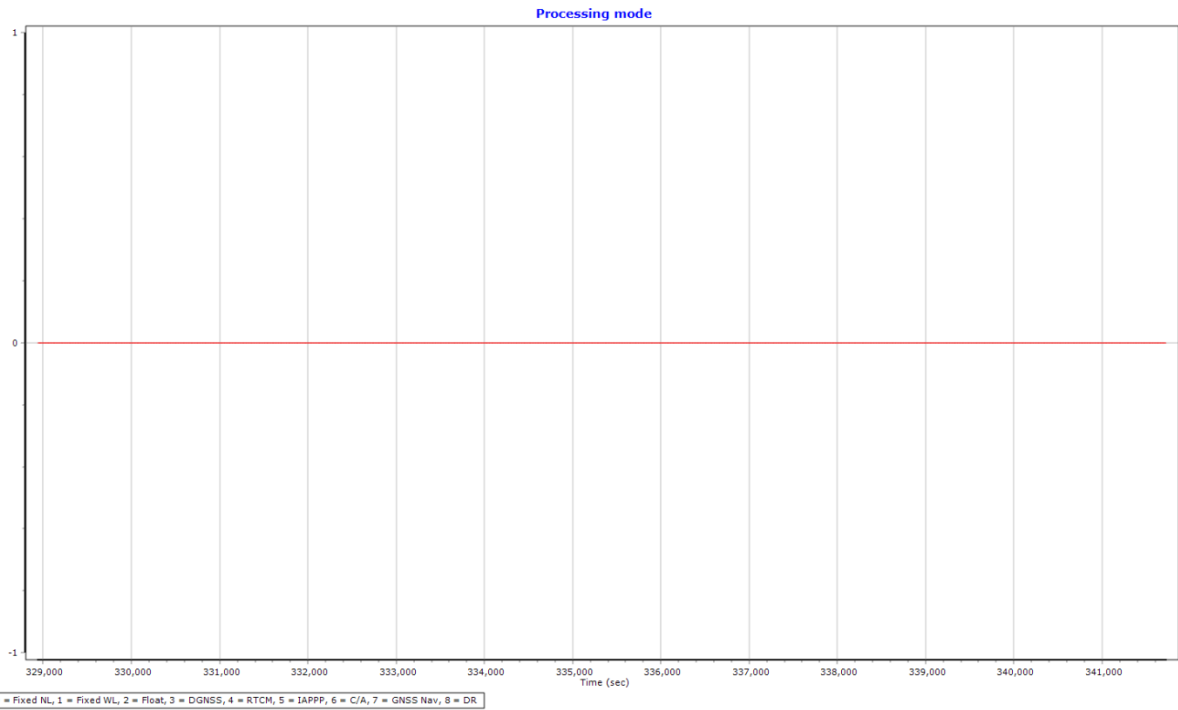
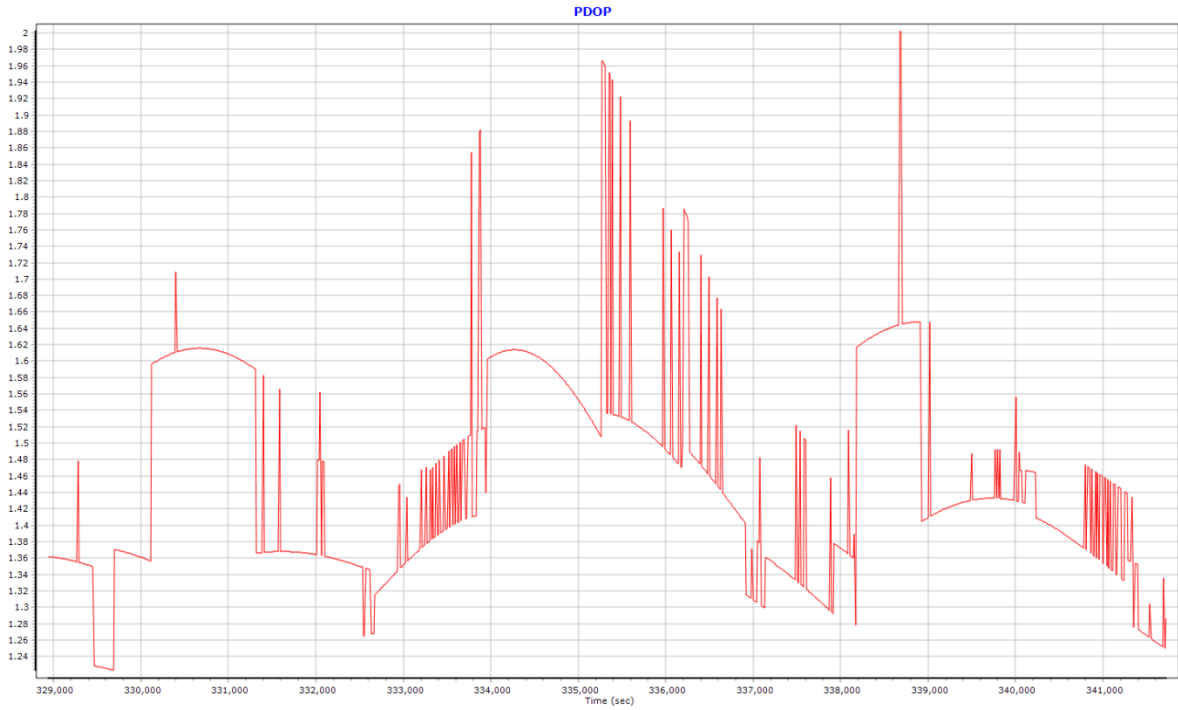
Z:

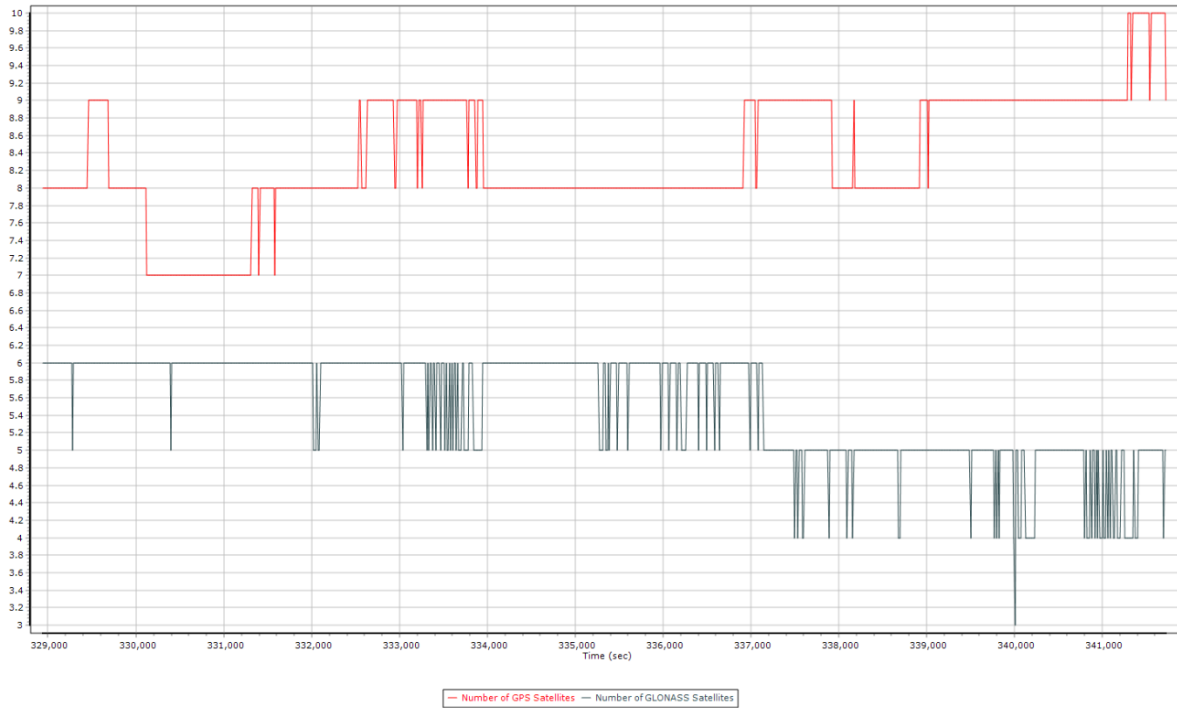
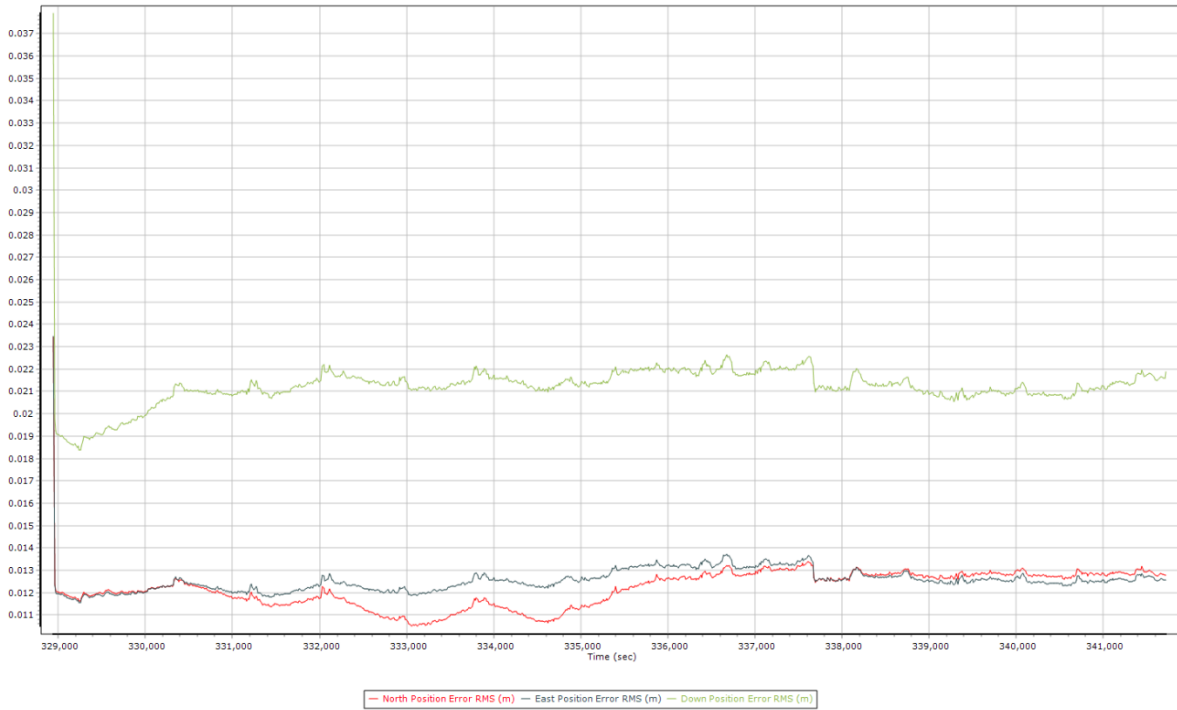
Standard Deviation

<3cm 10cm 50cm 1m 10m

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

OK Cancel





Project Settings [X]

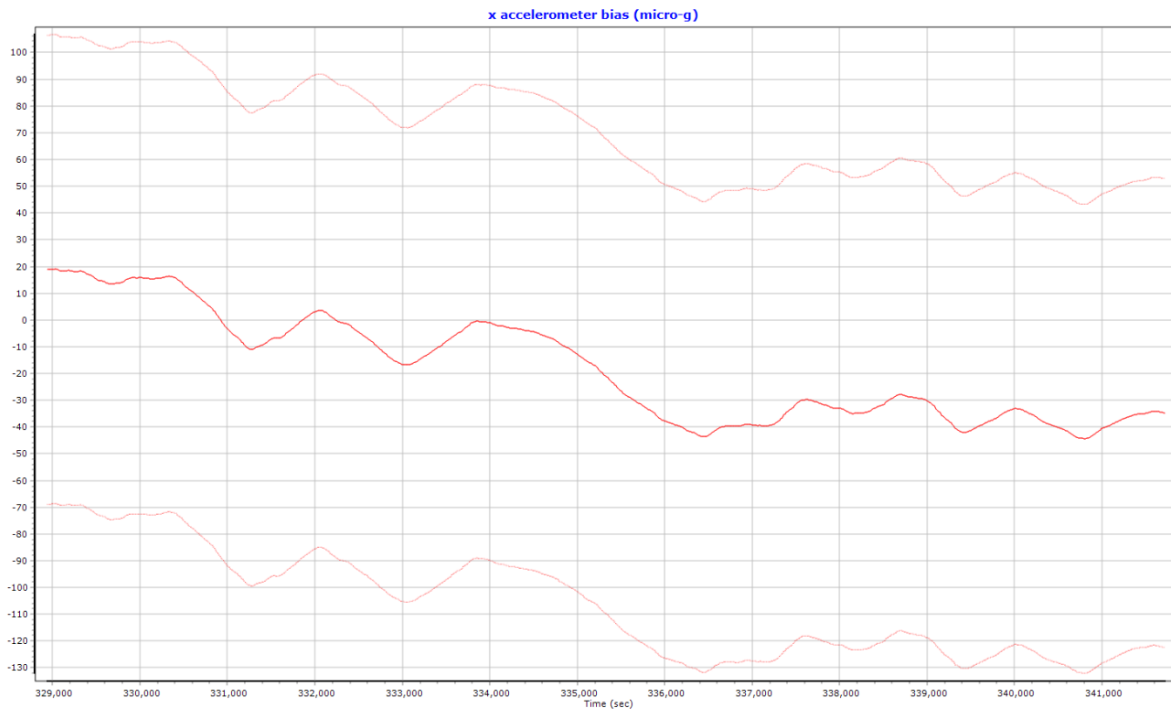
General Information
Units
View
Rover Import
Satellite Selection
GNSS-Inertial Processor
Timing
Algorithms
Initialization
Lever Arms and Mounting Angles
Export
Camera
LiDAR
SAR

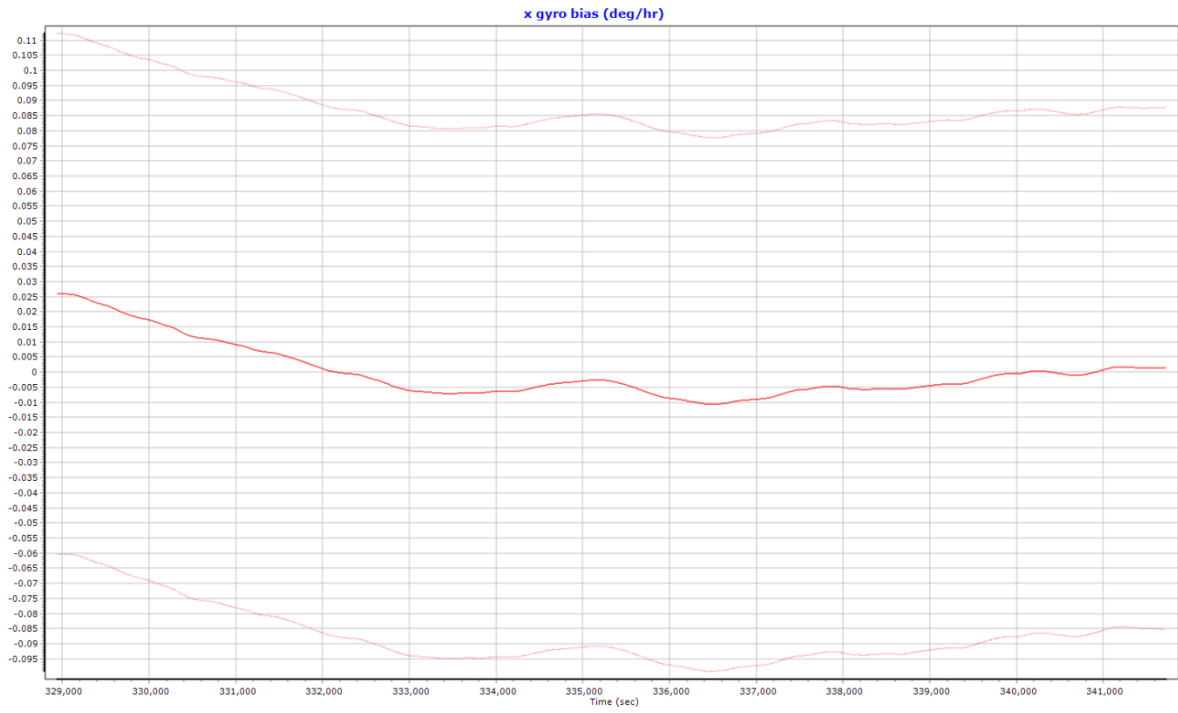
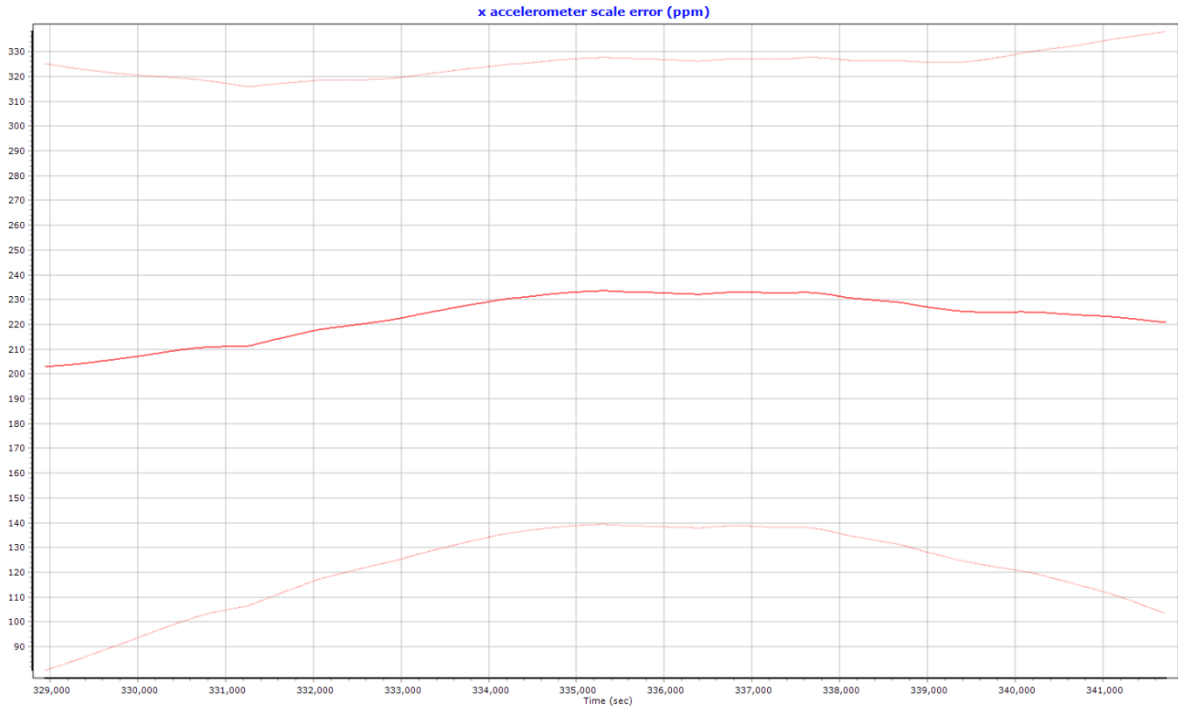
Timing

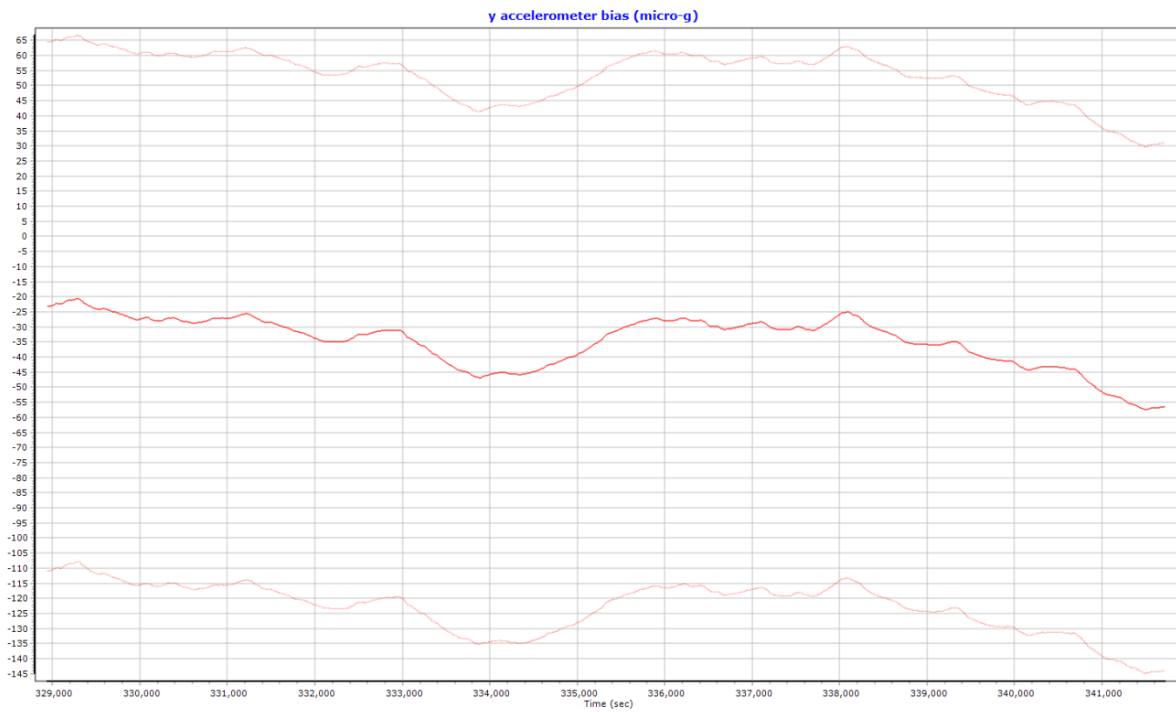
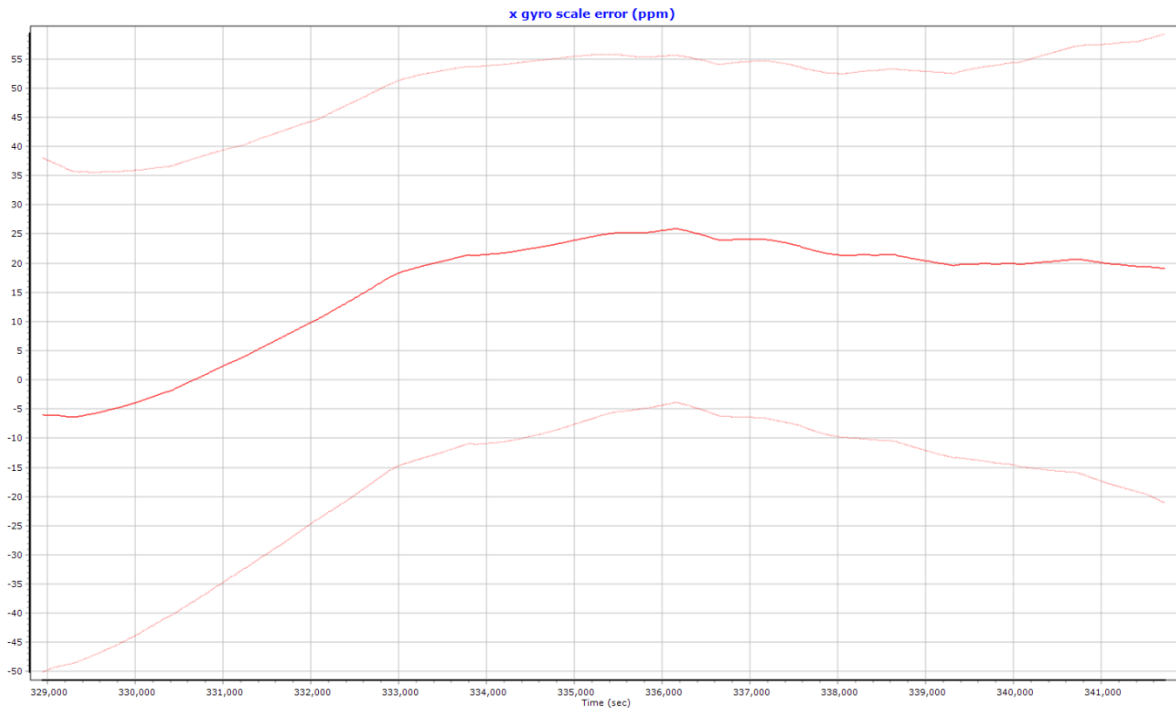
Start: 328939.074
End: 341744.047
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

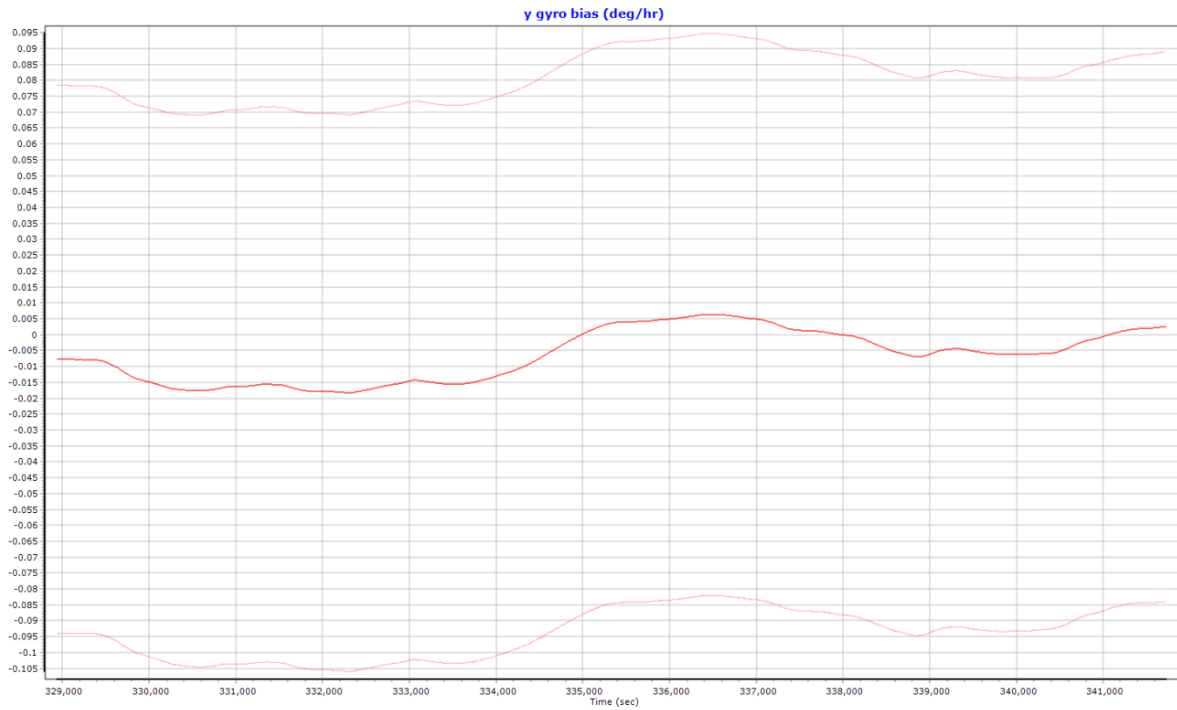
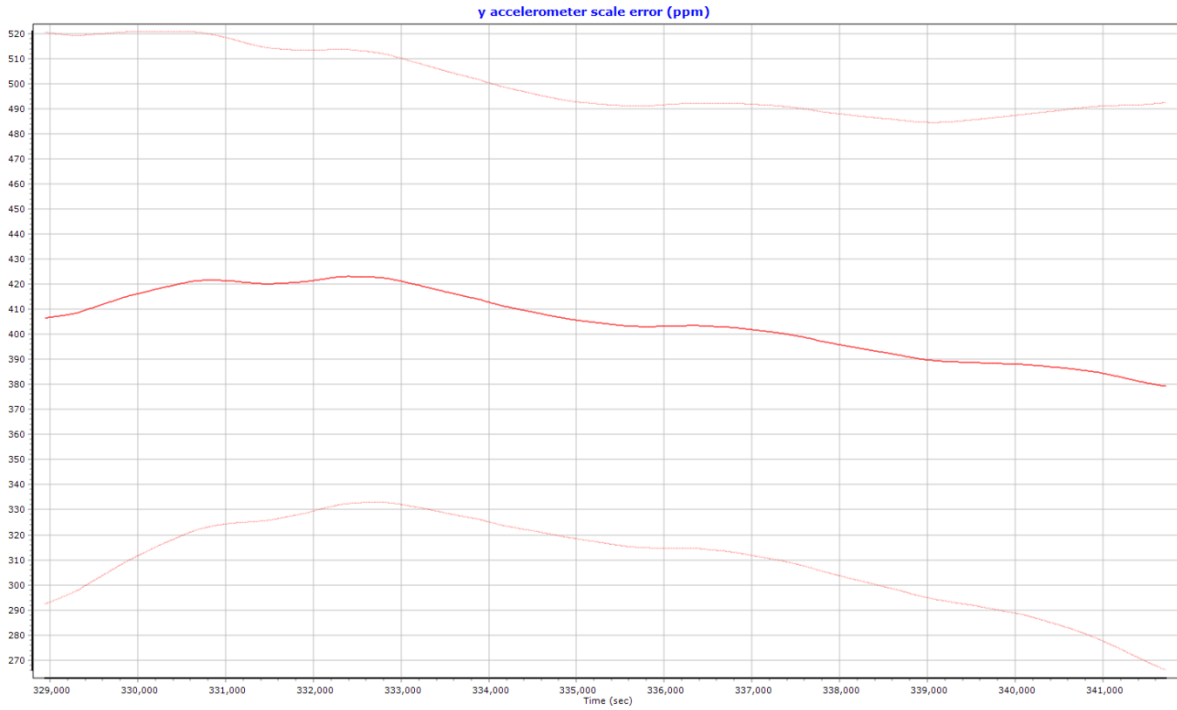
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

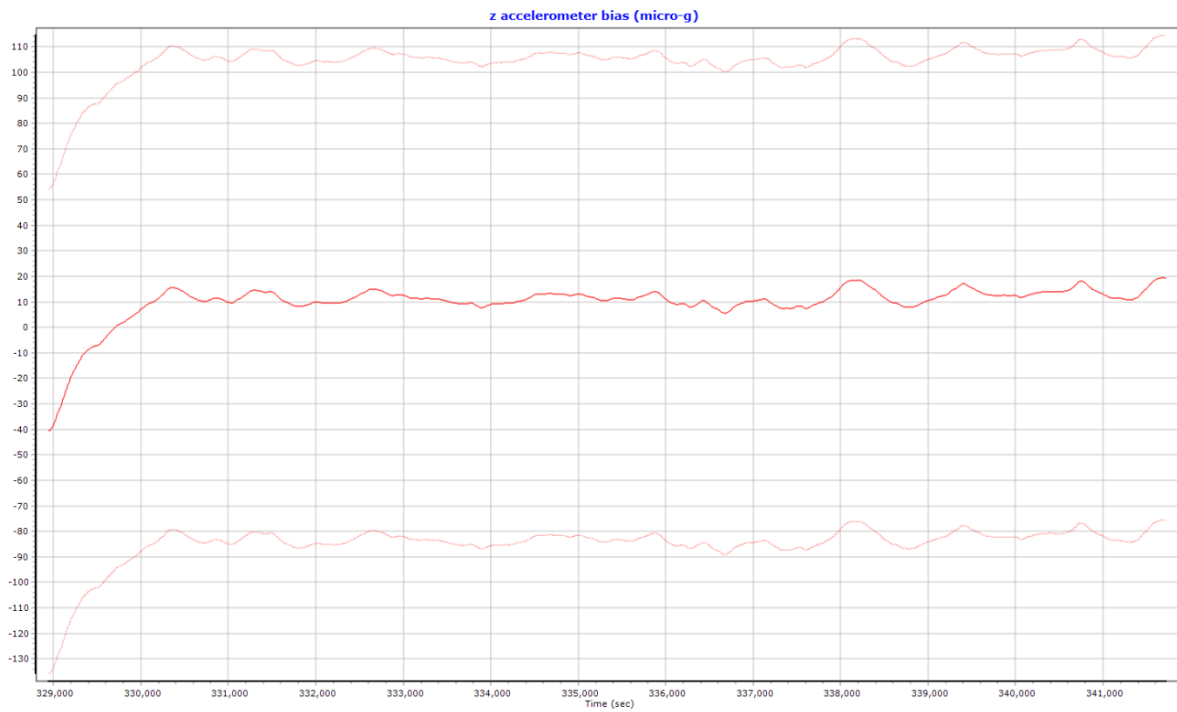
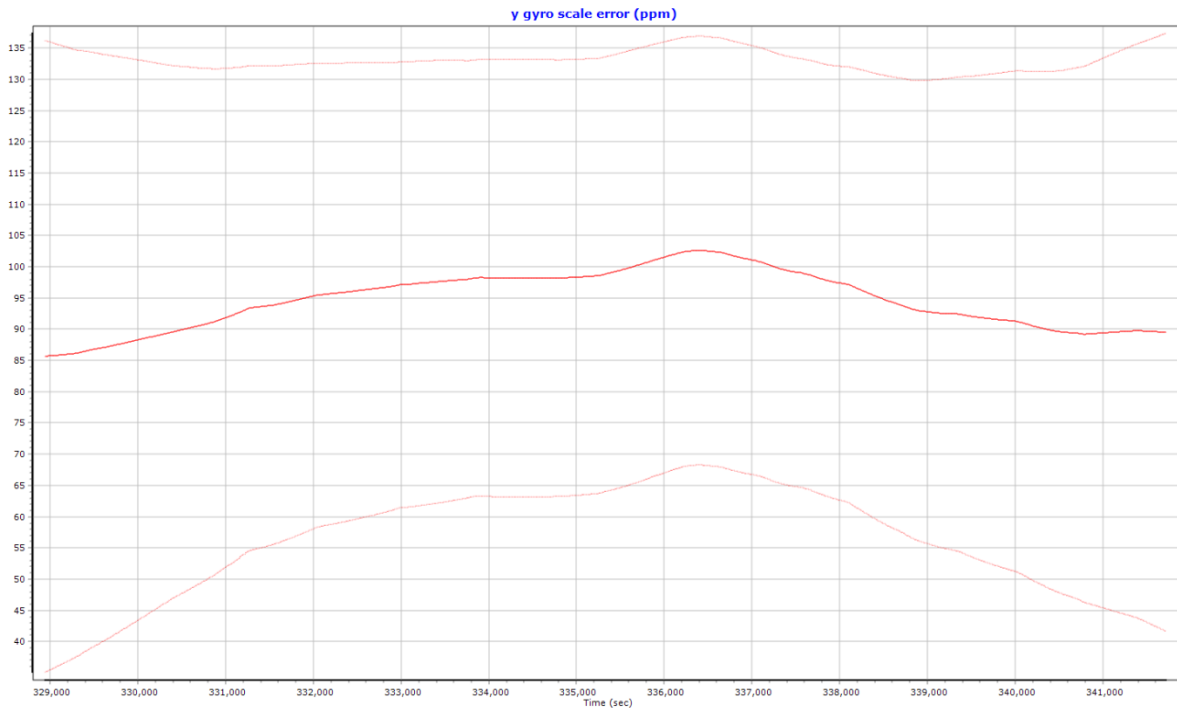
OK Cancel

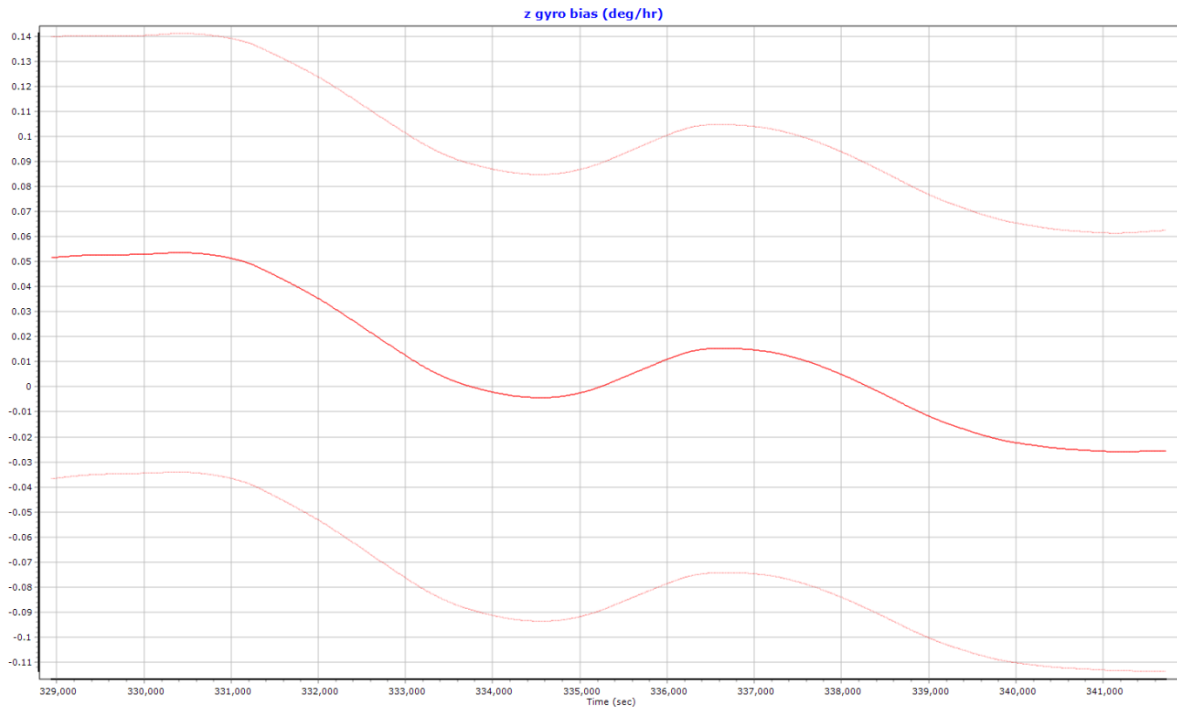
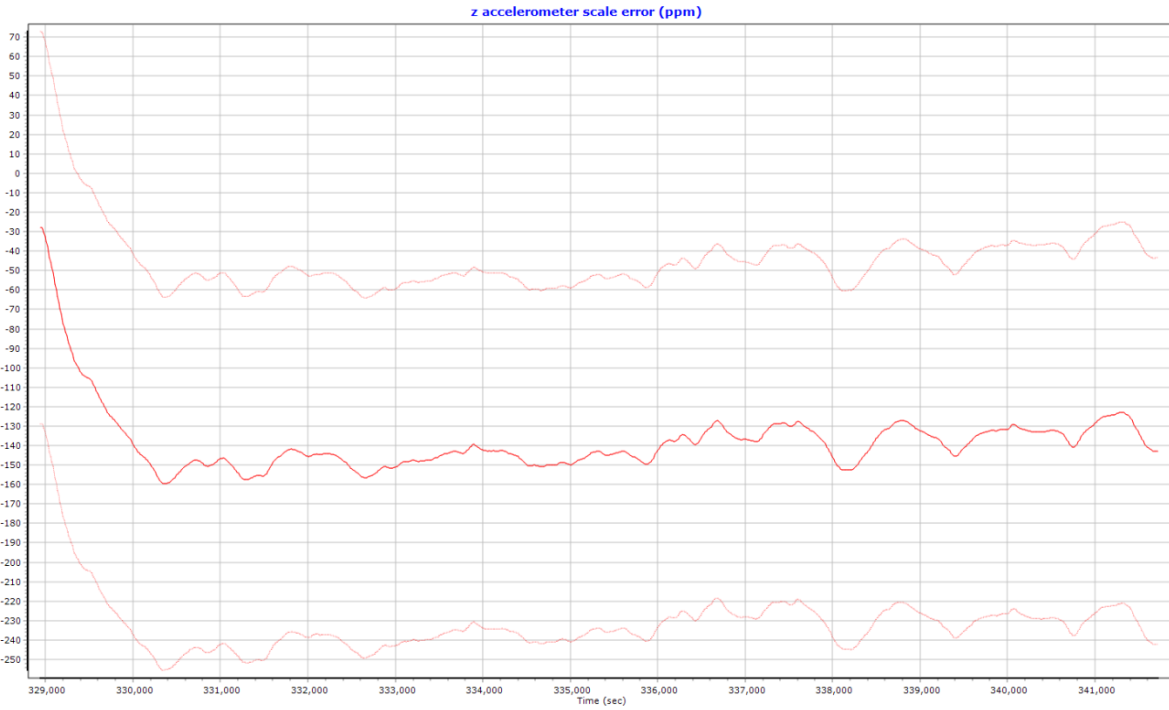


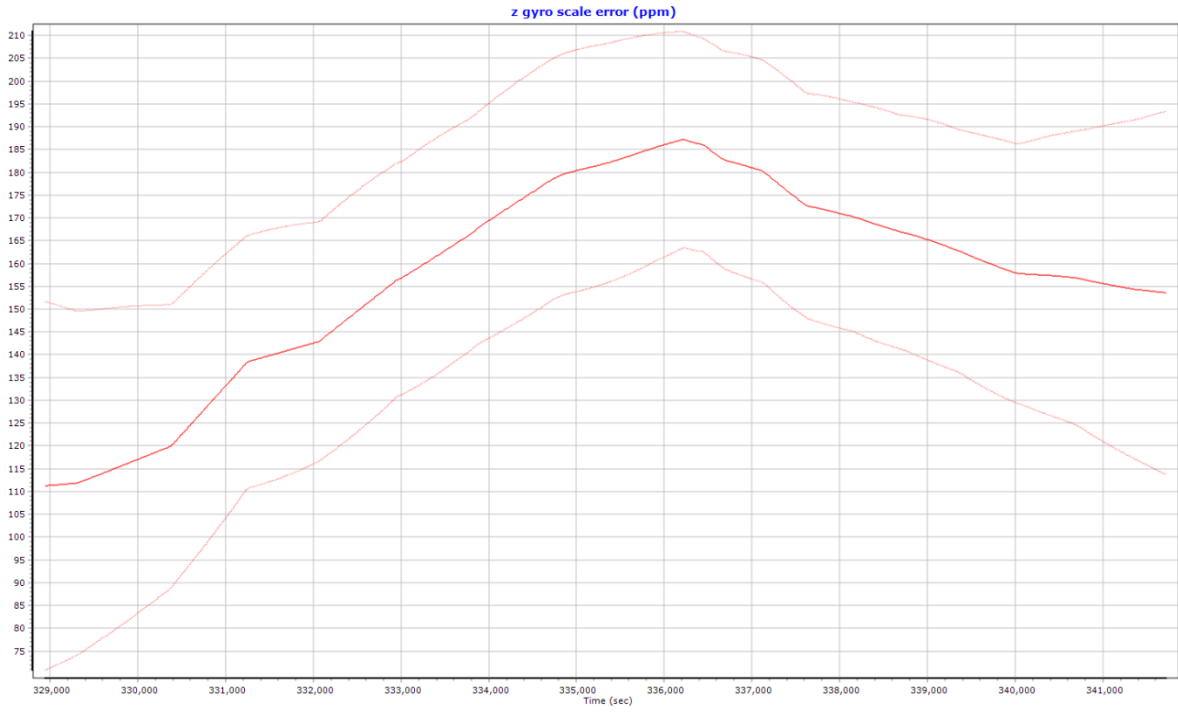




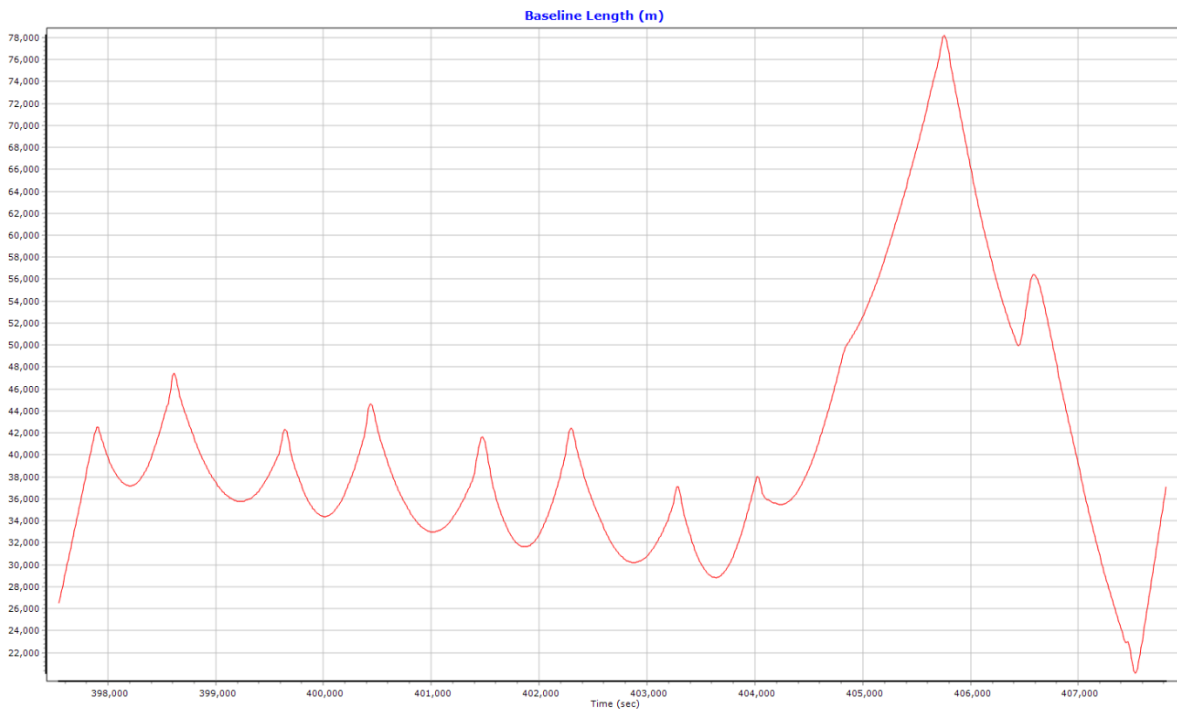
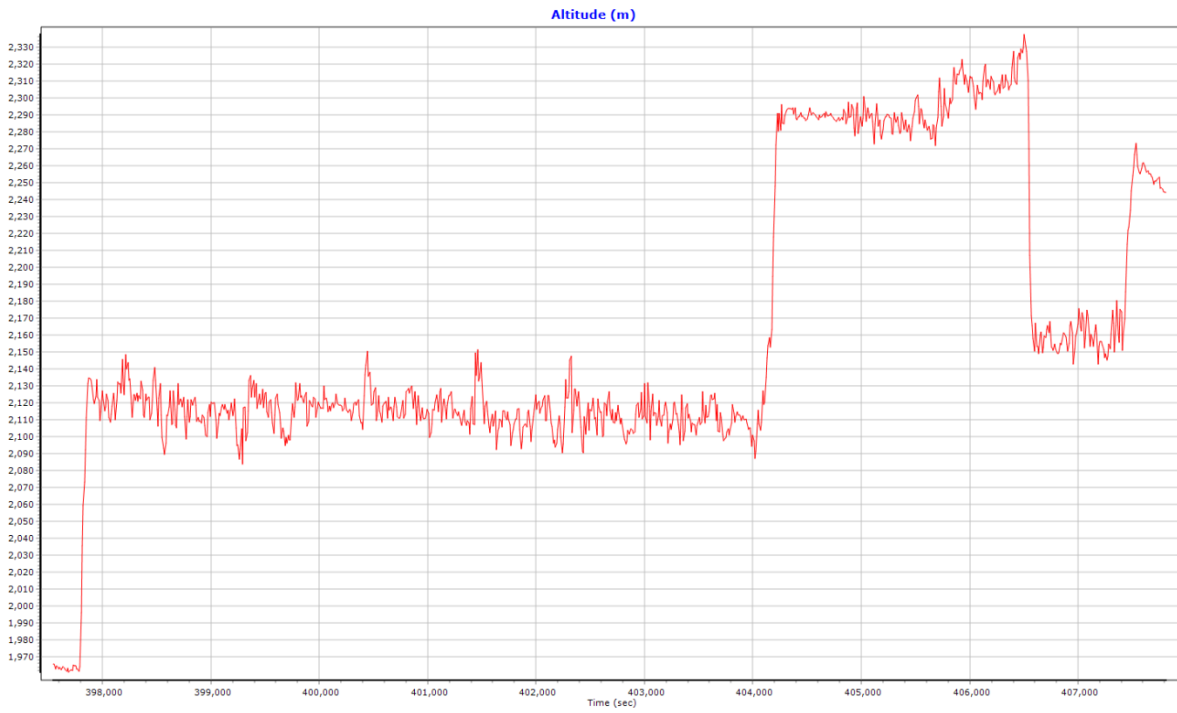


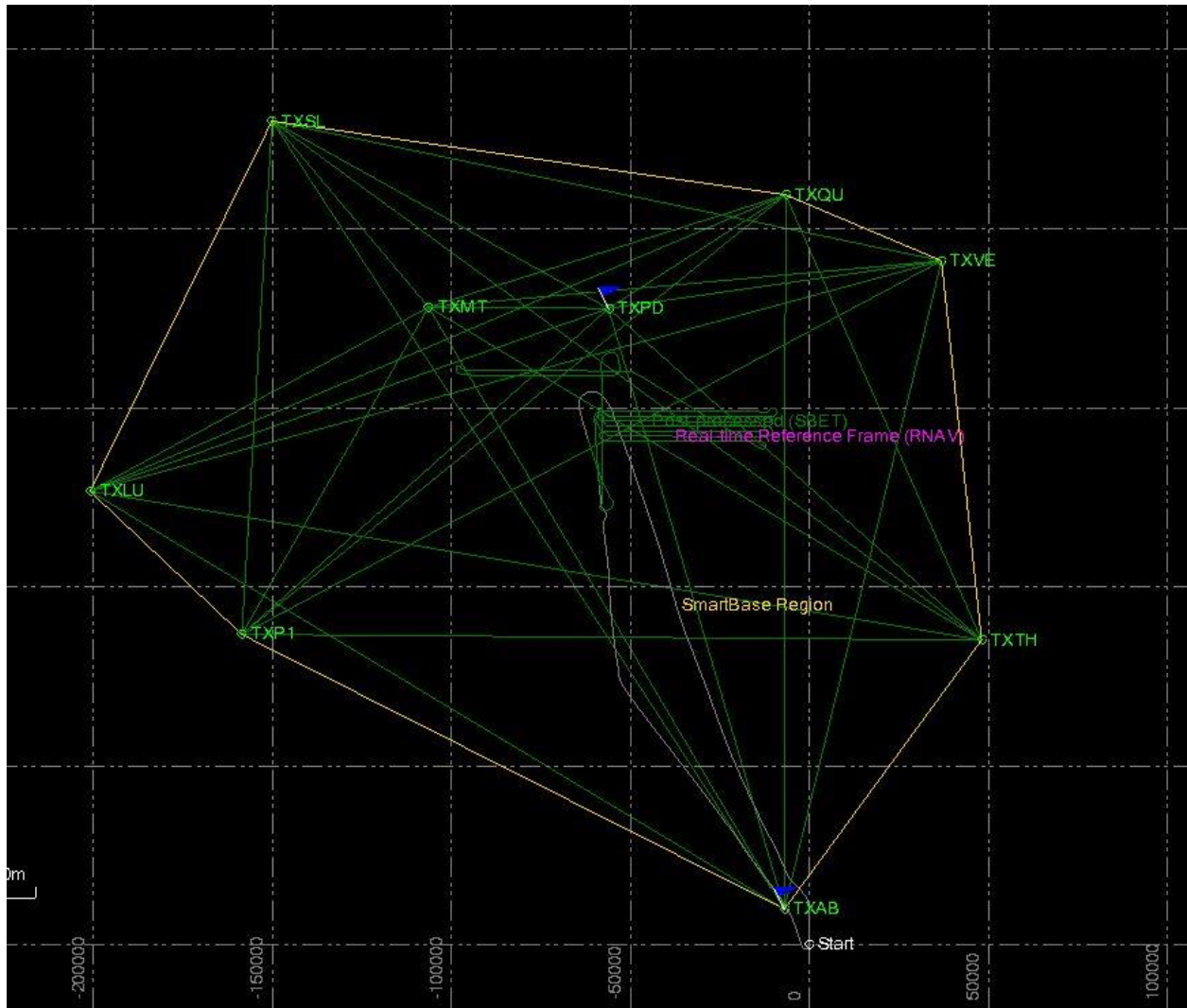






RBV18074A







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:

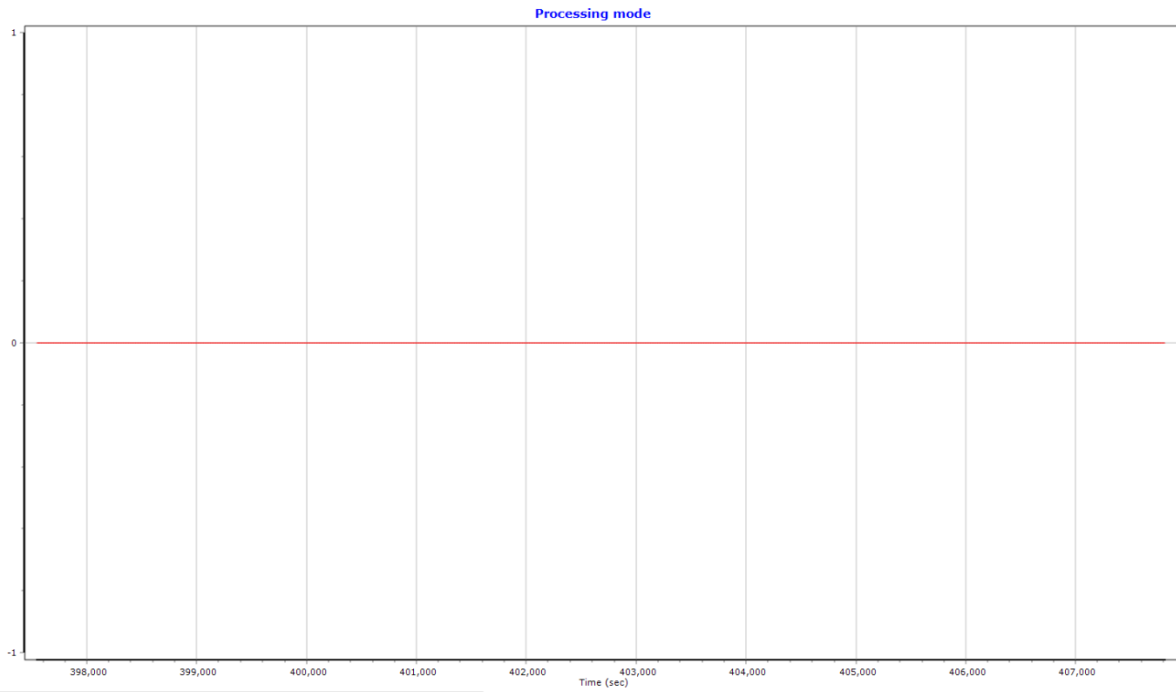
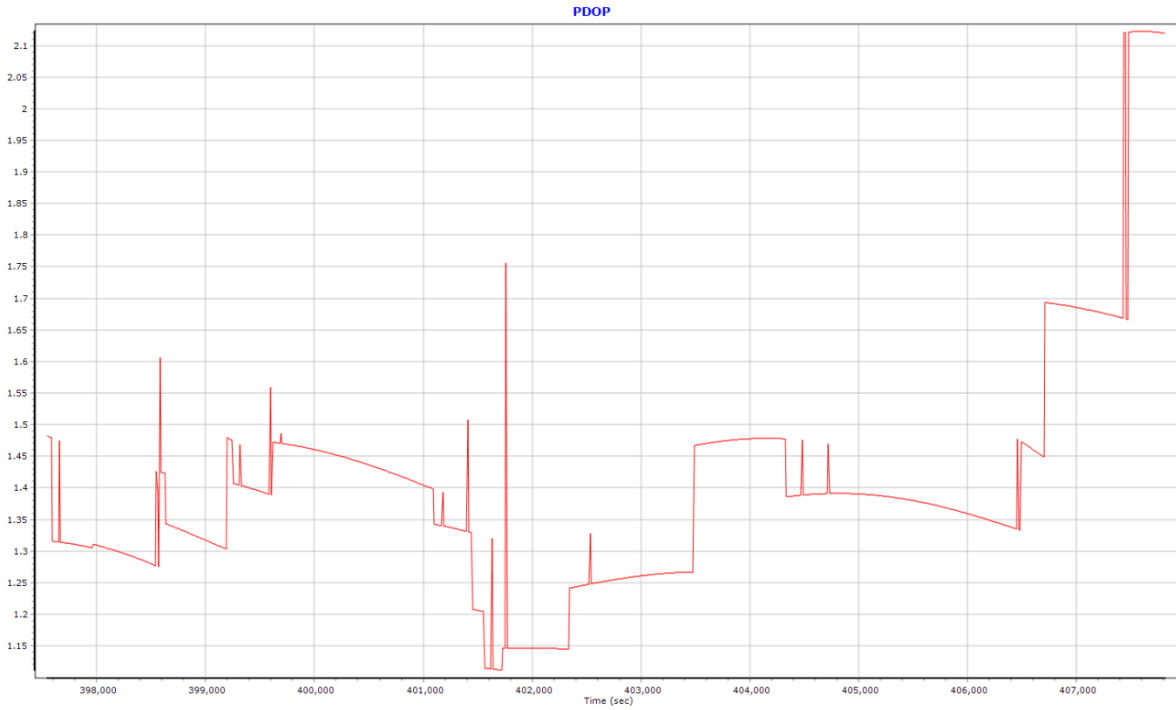
Z:

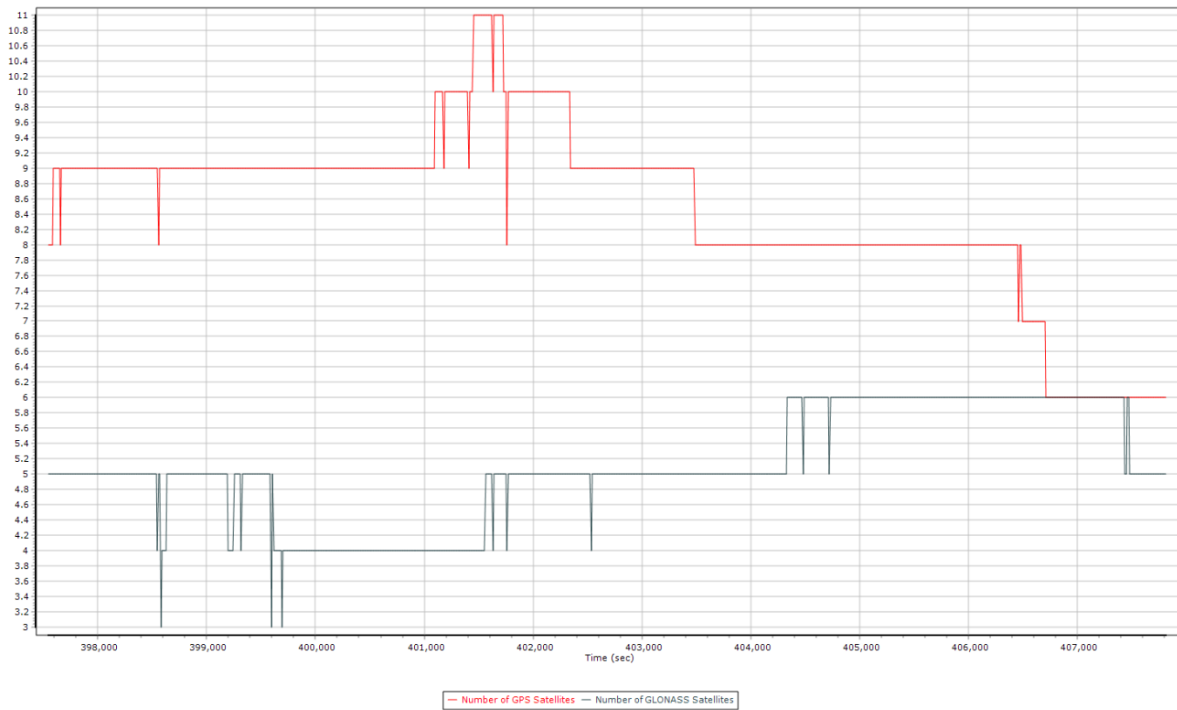
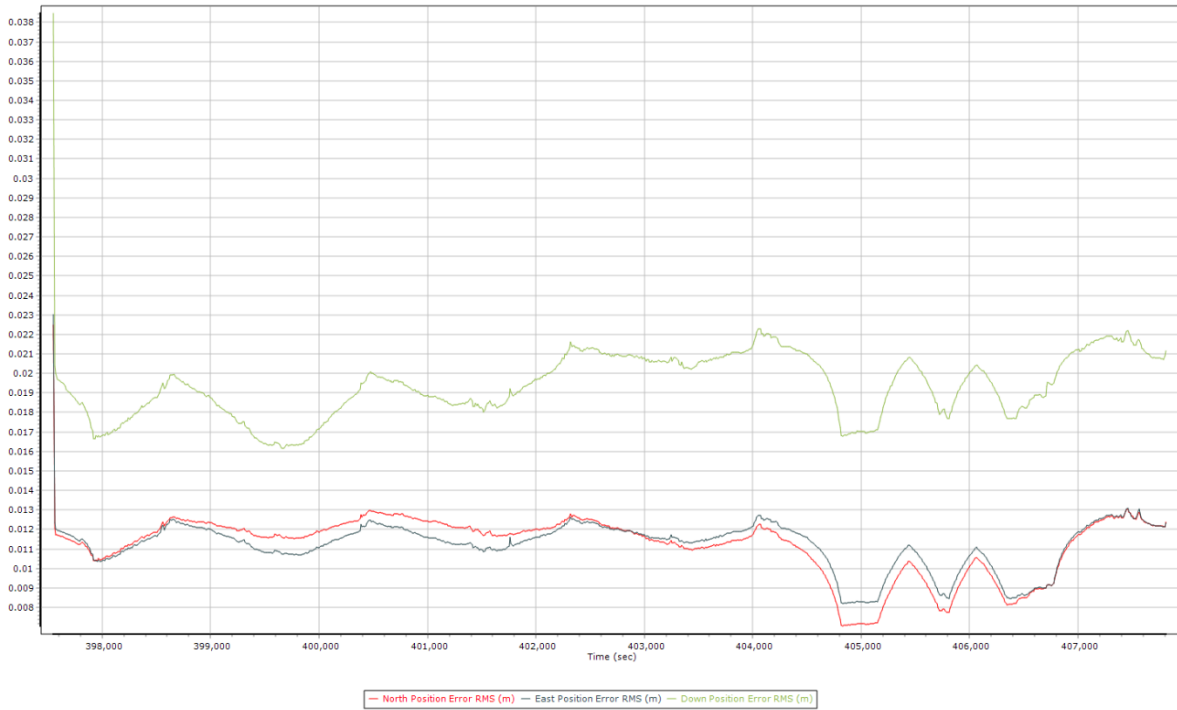
Standard Deviation

<3cm 10cm 50cm 1m 10m

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

OK Cancel





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

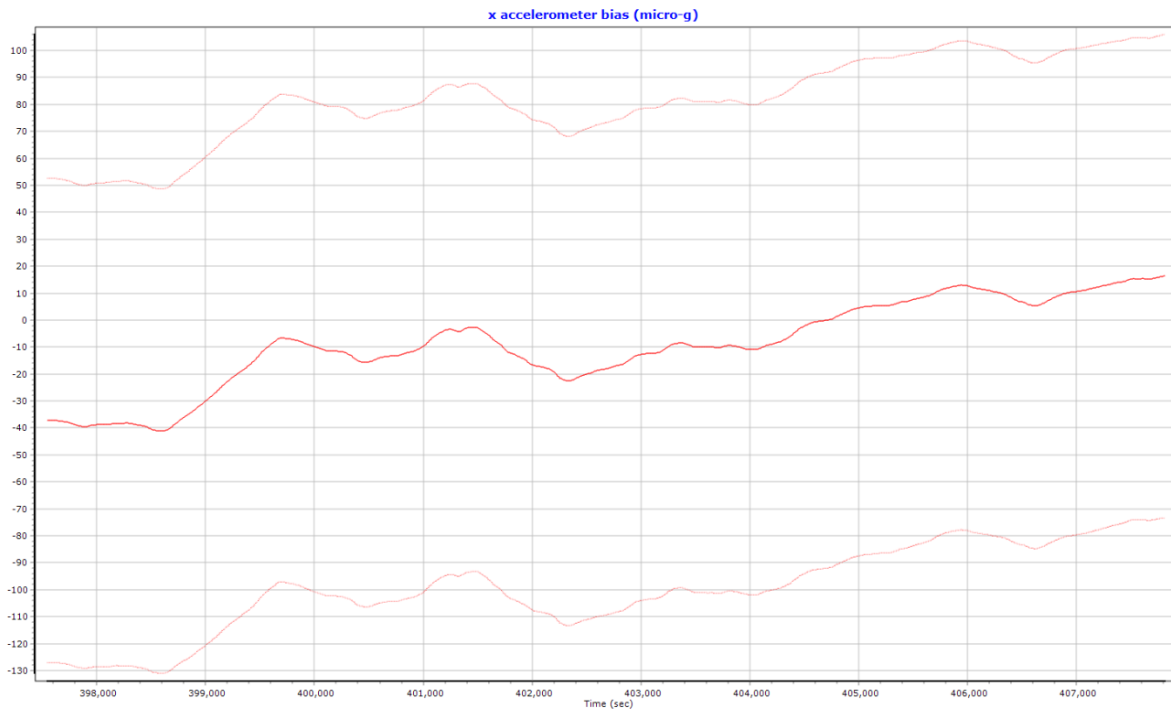
Start: 397545.427
End: 407825.808

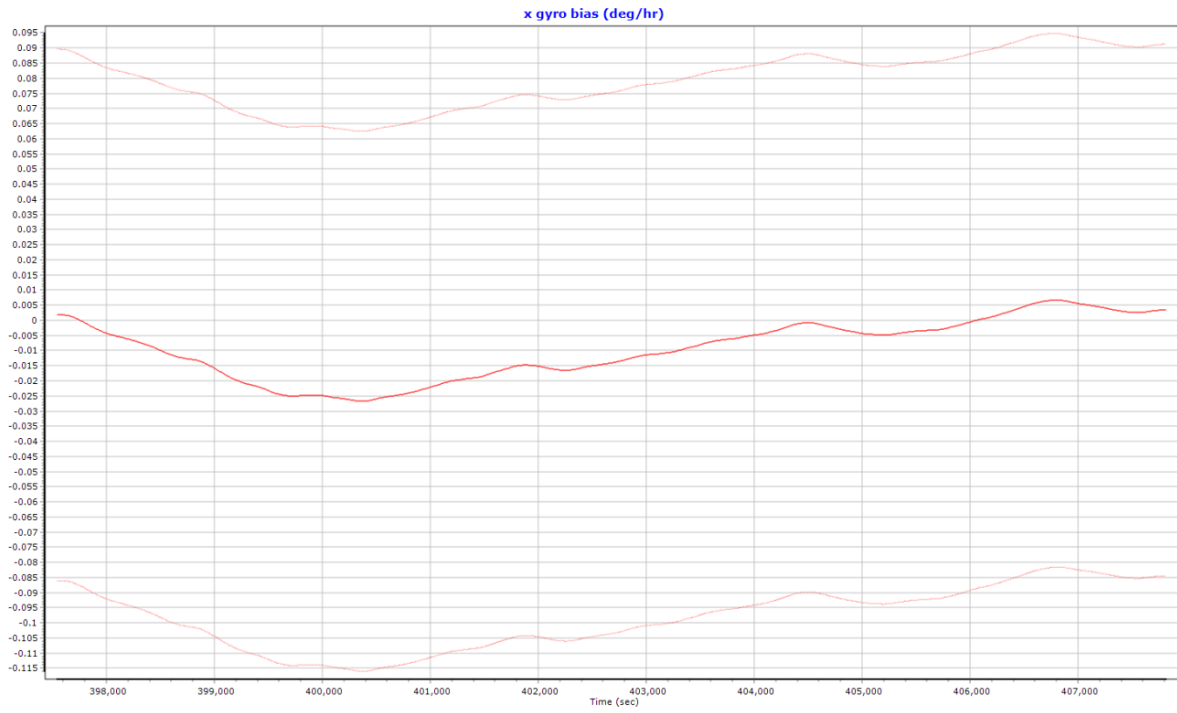
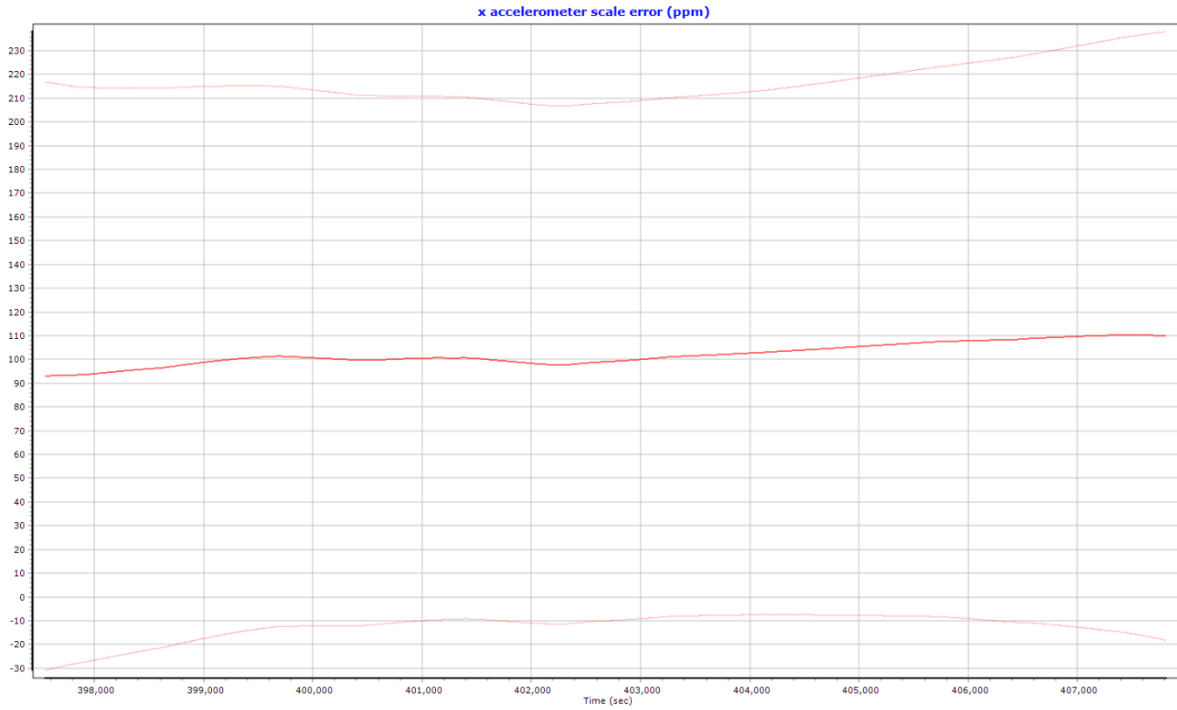
Entire time interval
 Seconds of start week

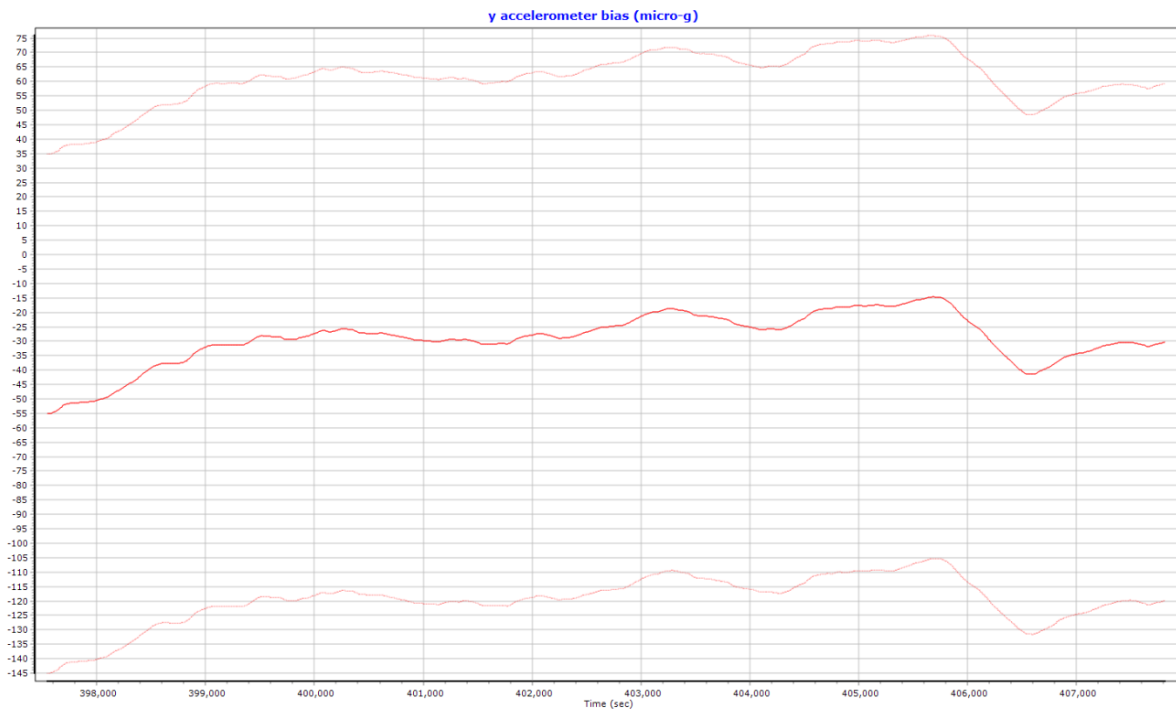
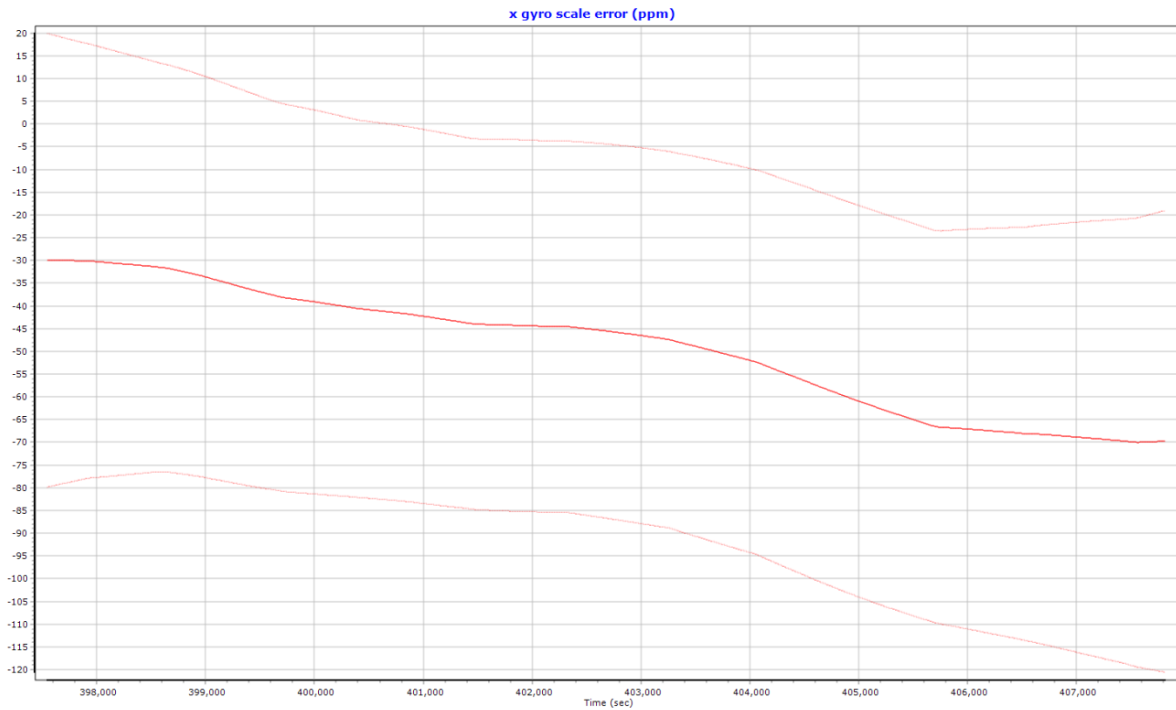
UTC Offset: 18.000

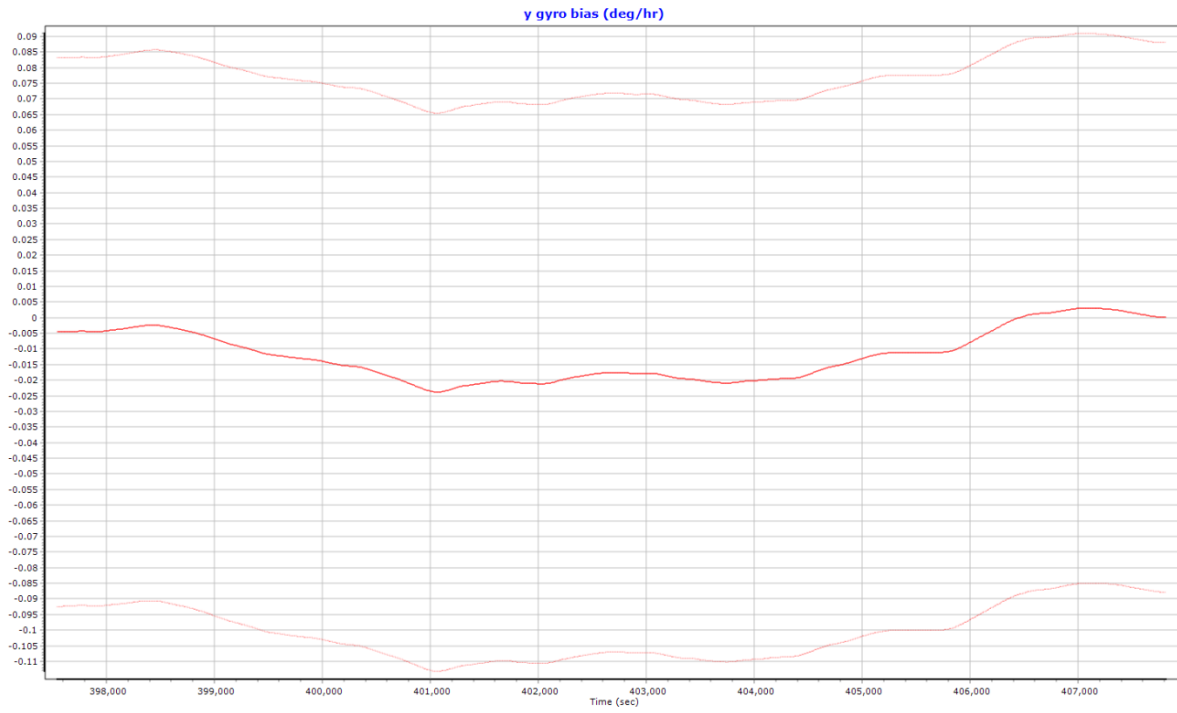
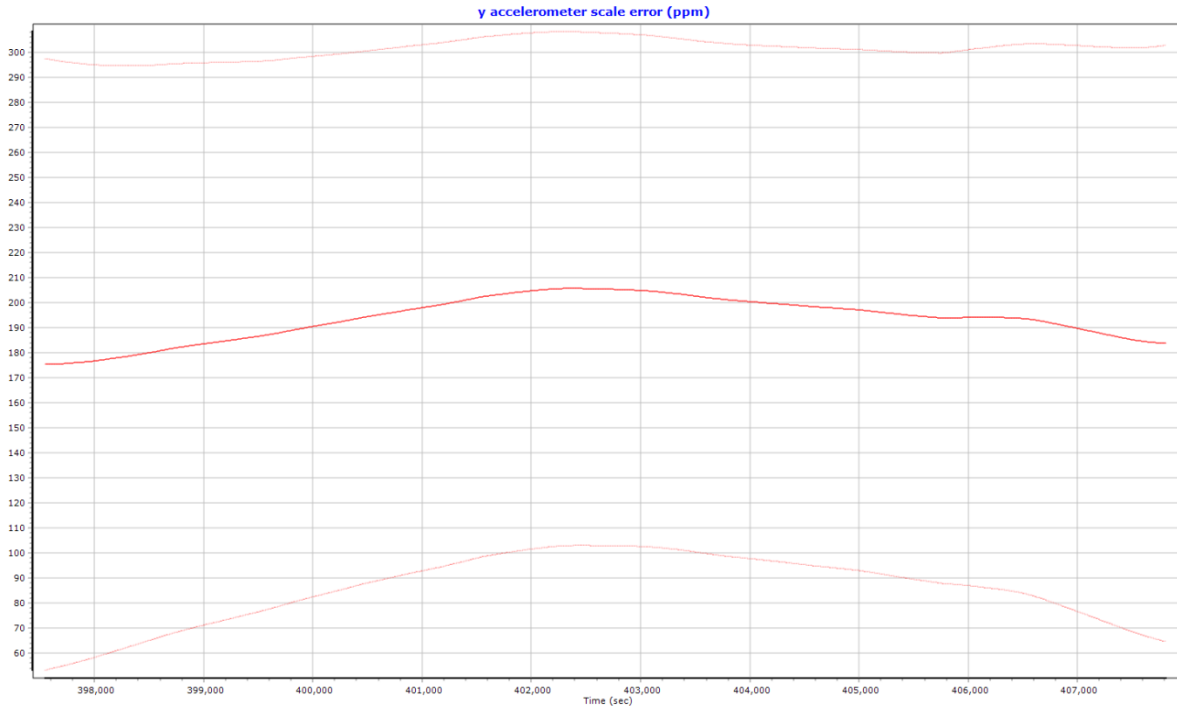
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

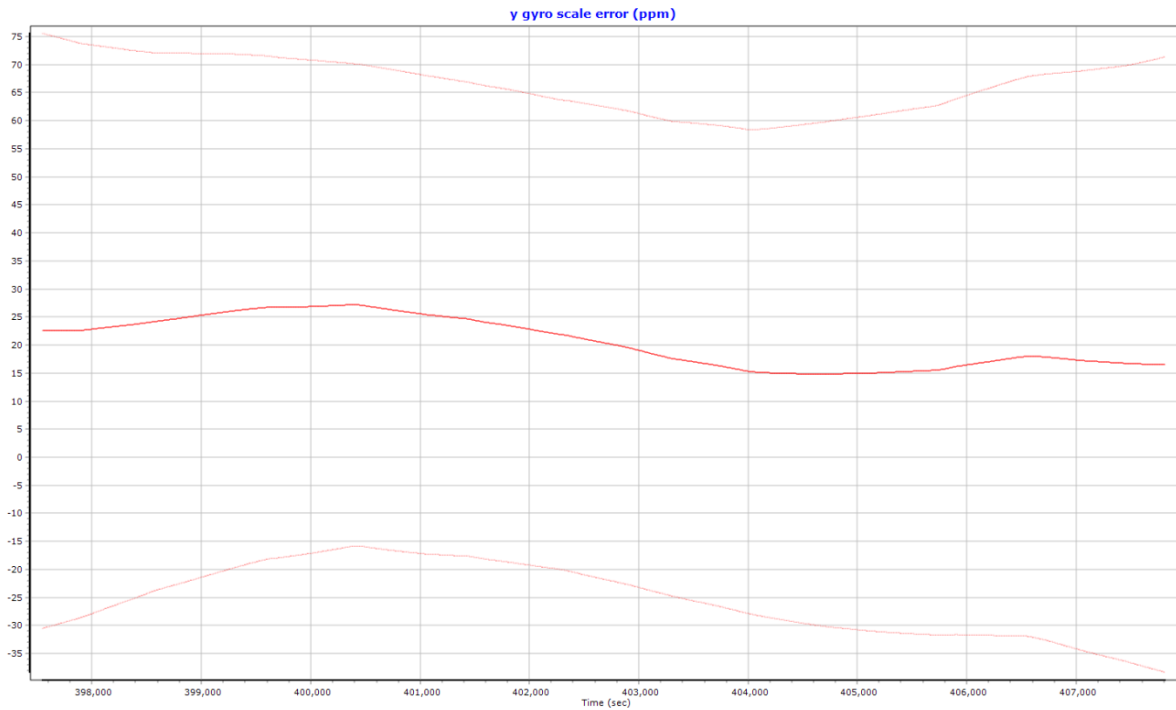
OK Cancel

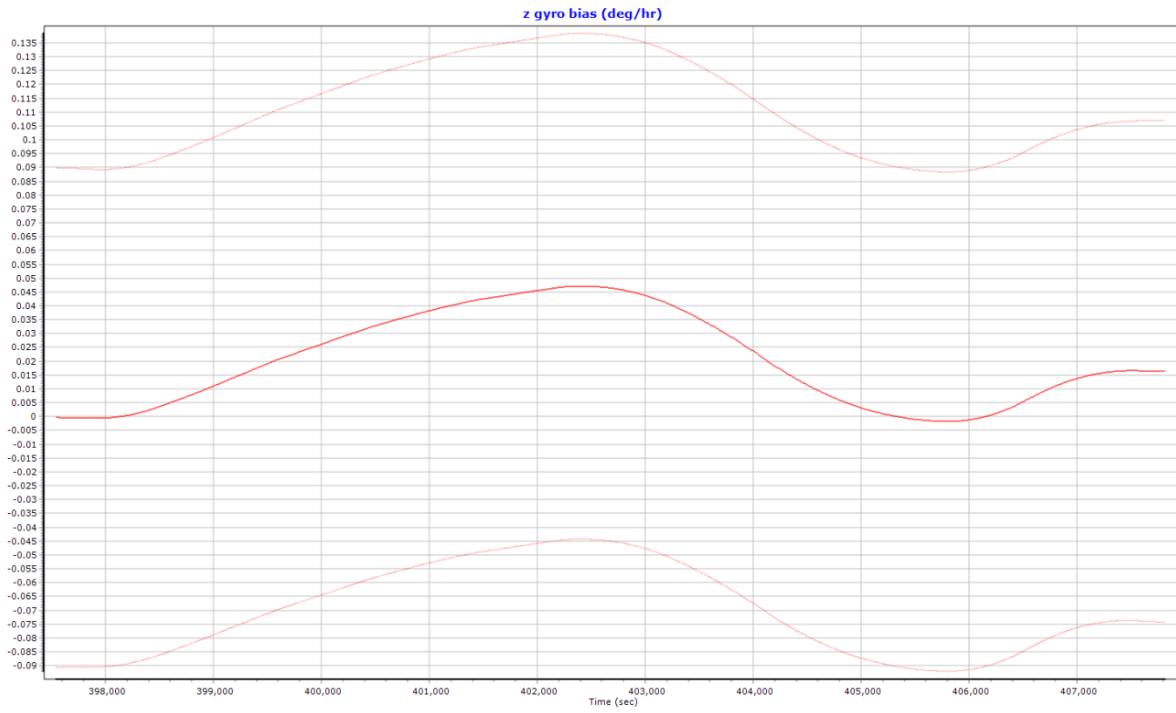
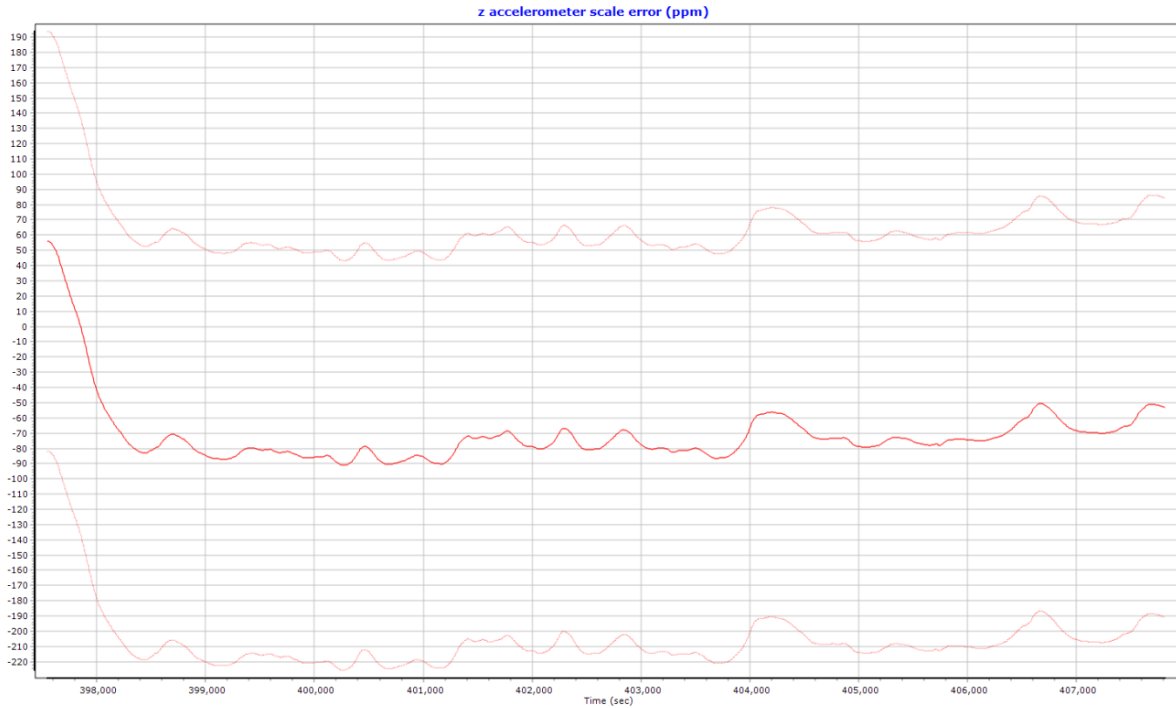


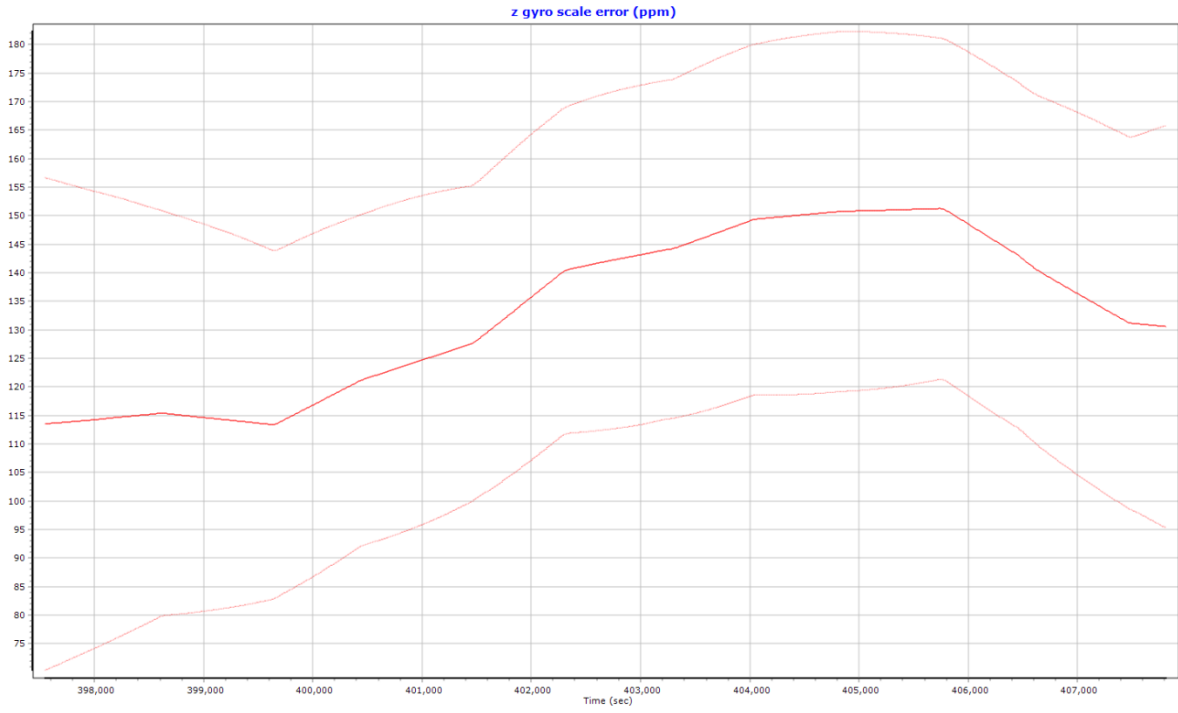




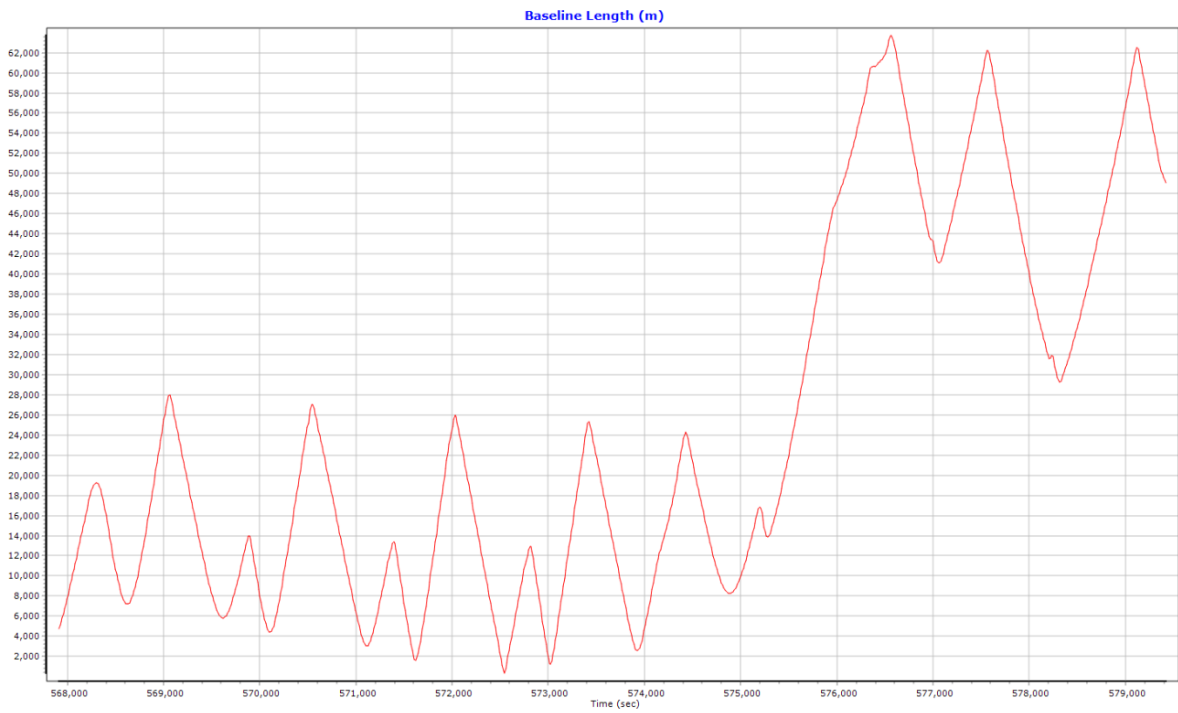
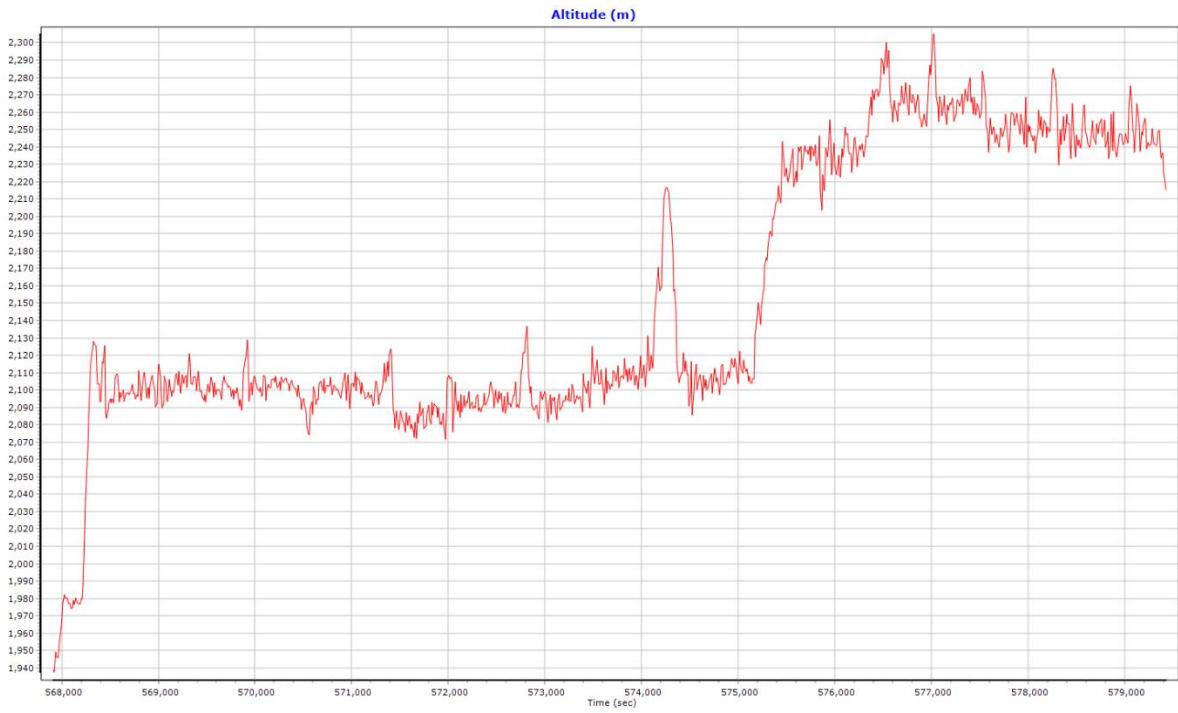


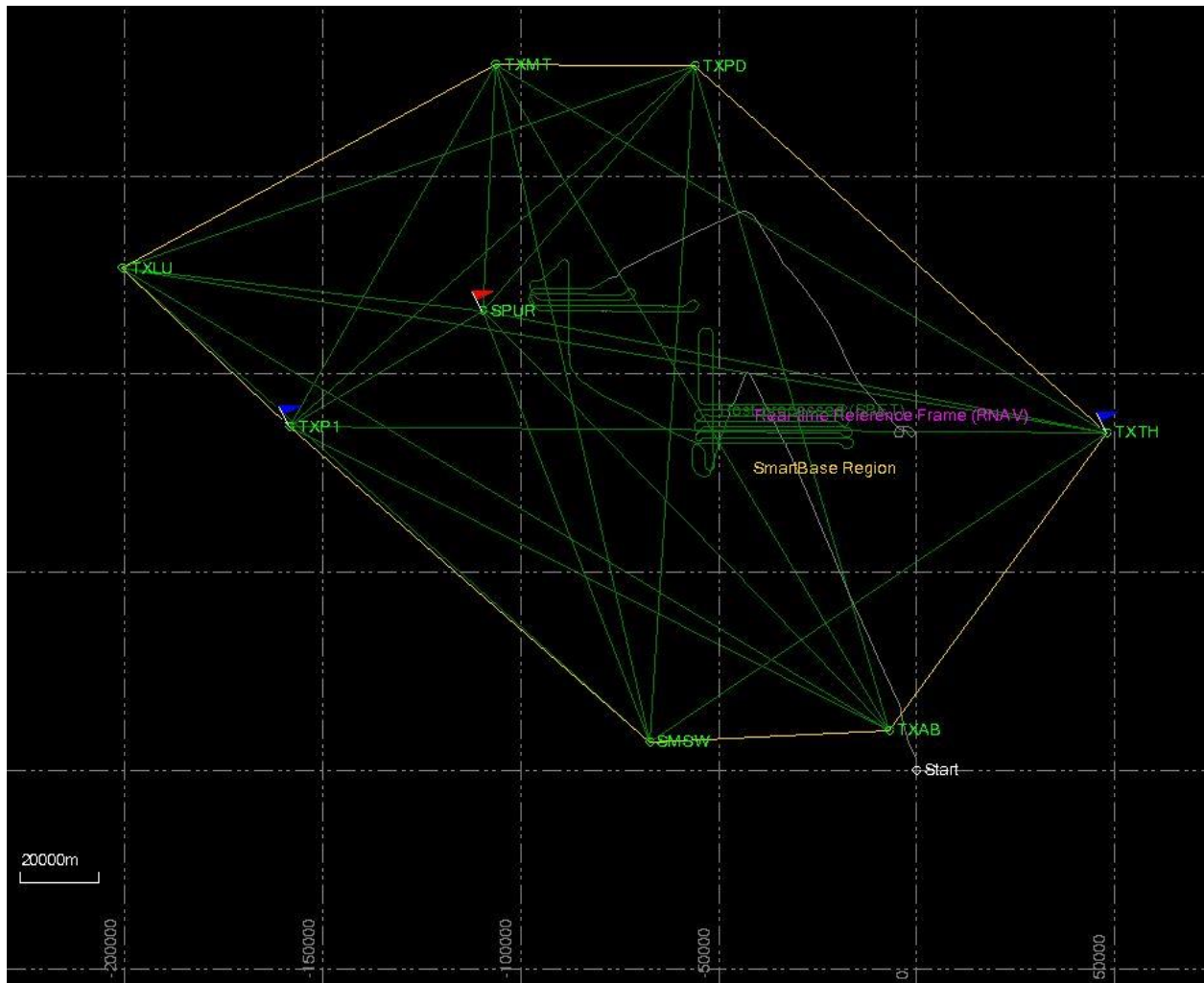


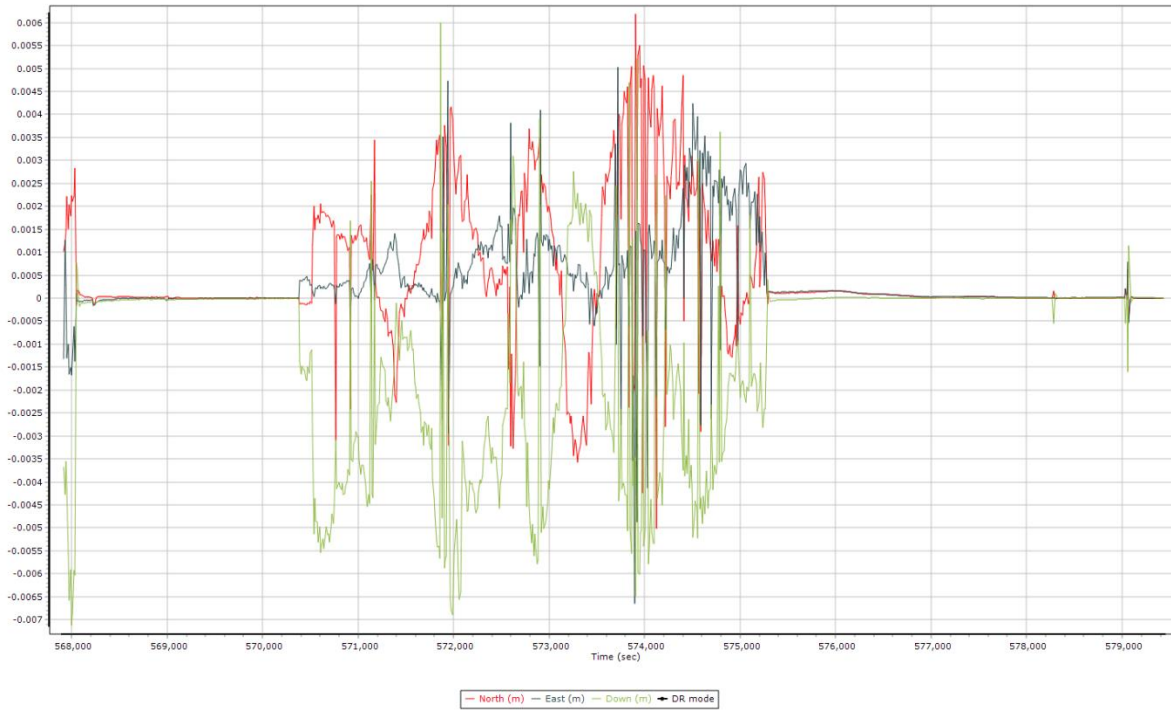




RBV18076A







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

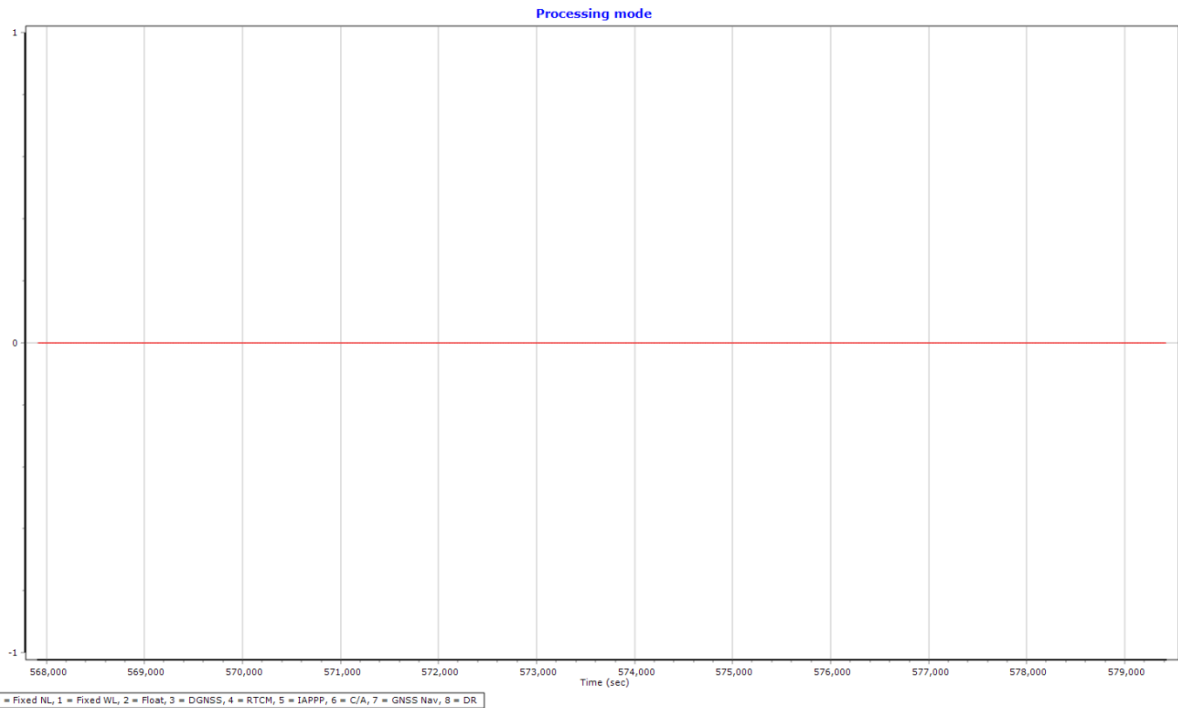
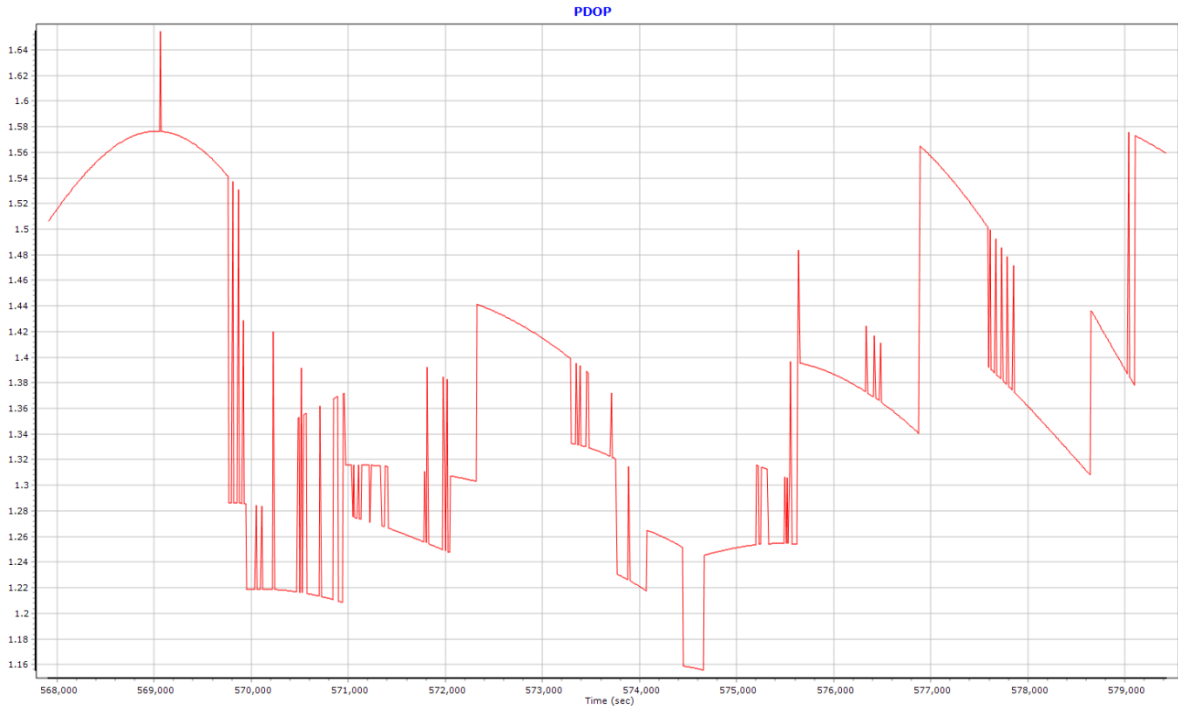
X:

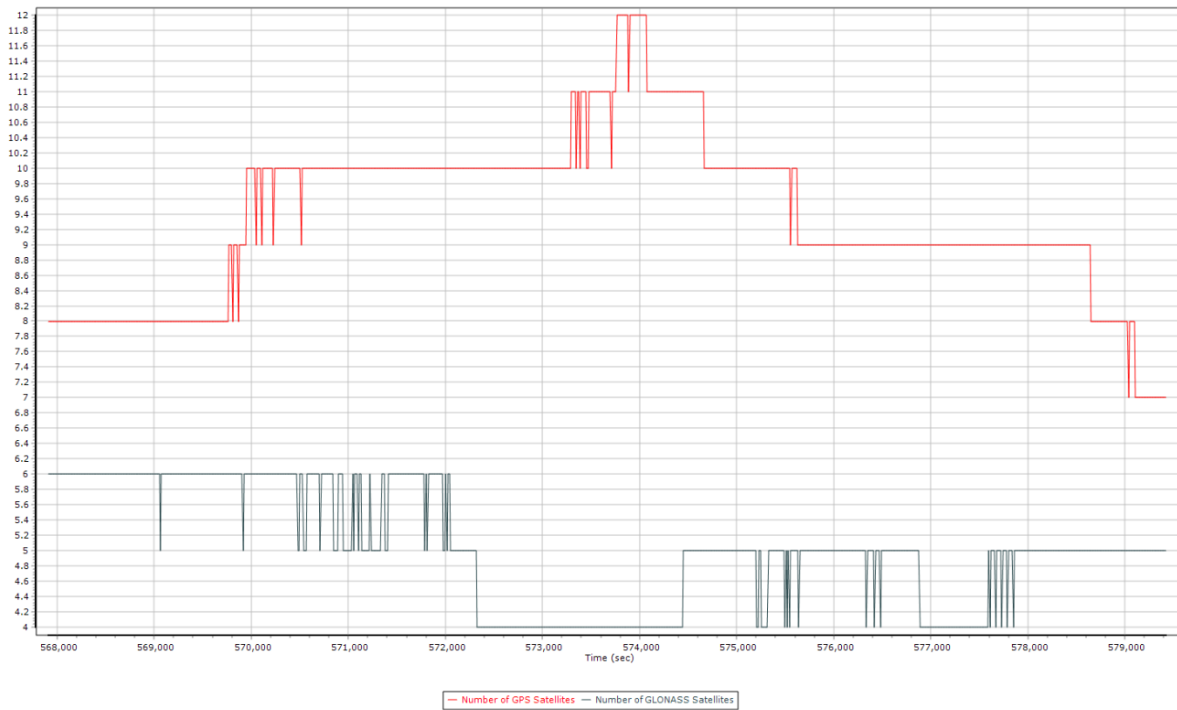
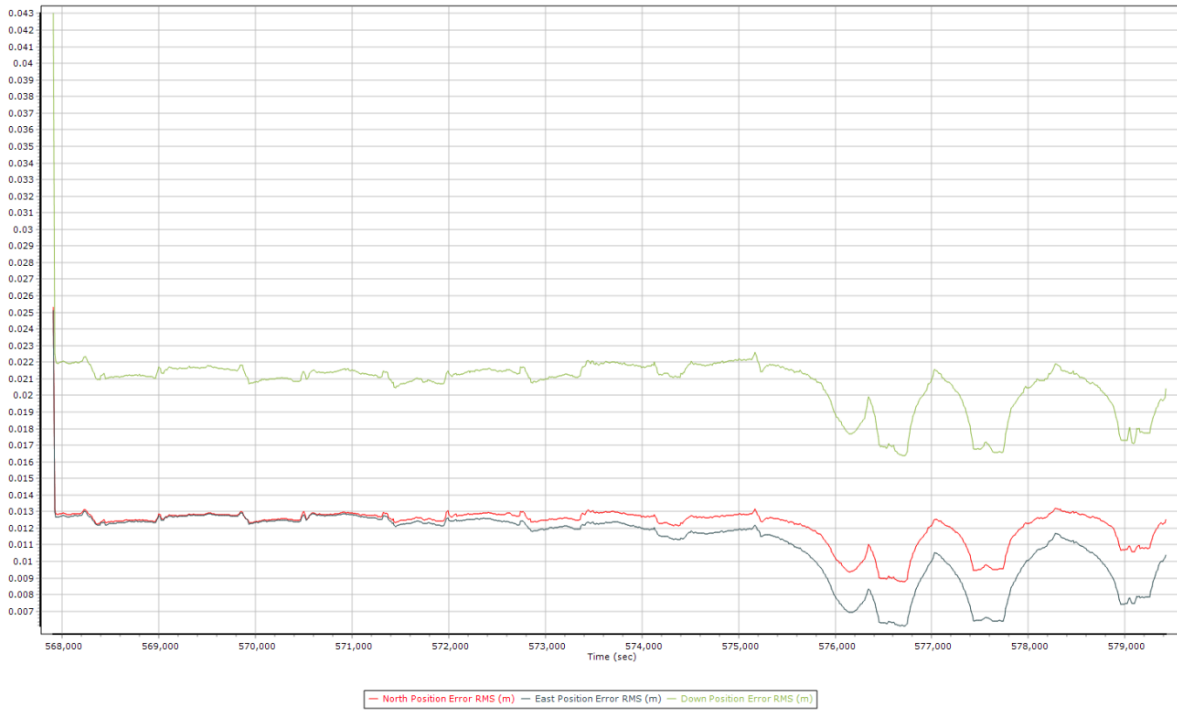
Y:

Z:

Standard Deviation:

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

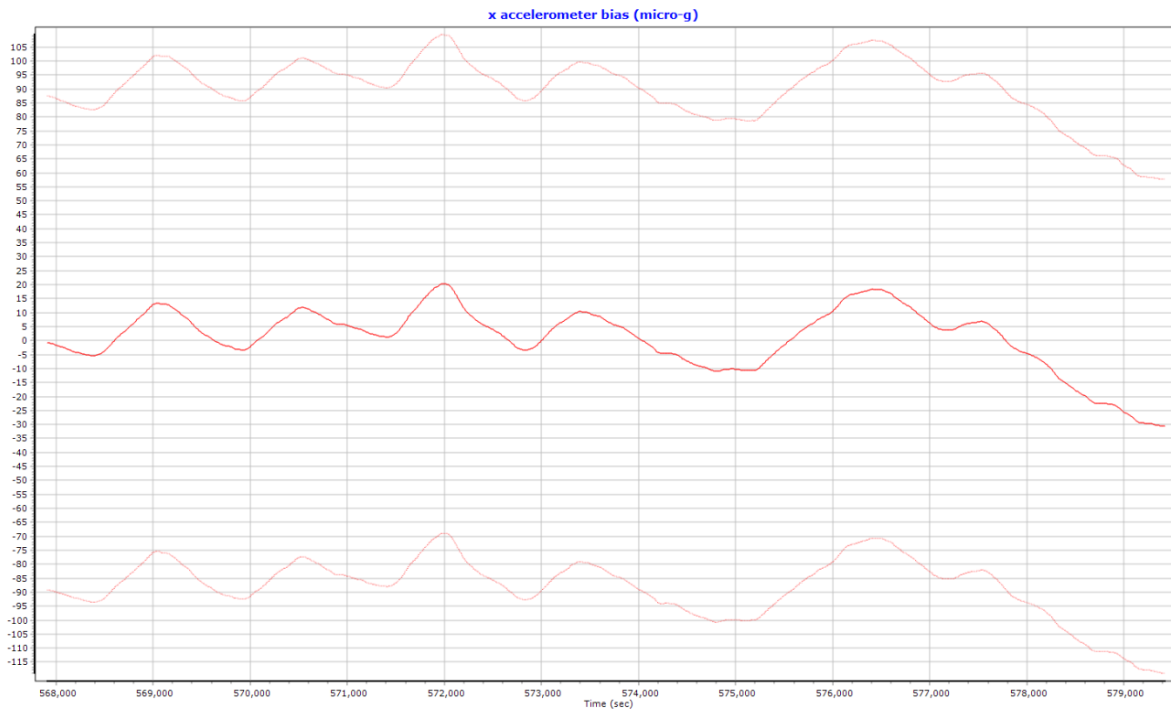
Start: 567910.010
End: 579438.678

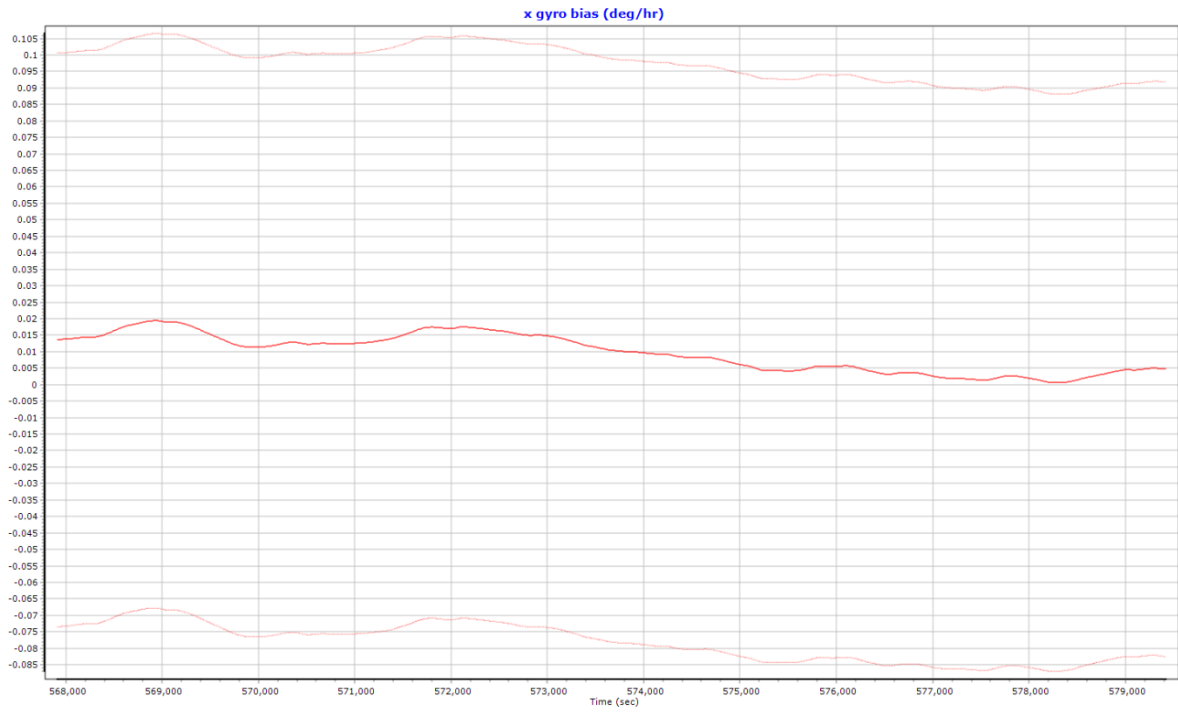
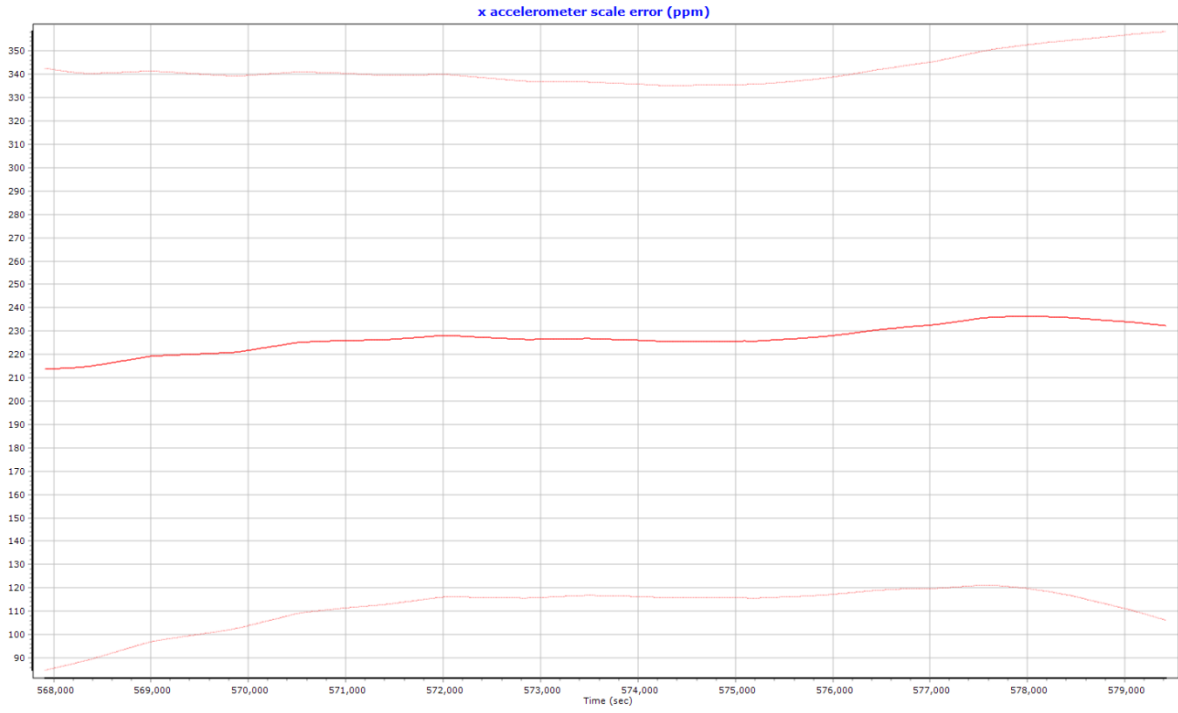
Entire time interval
 Seconds of start week

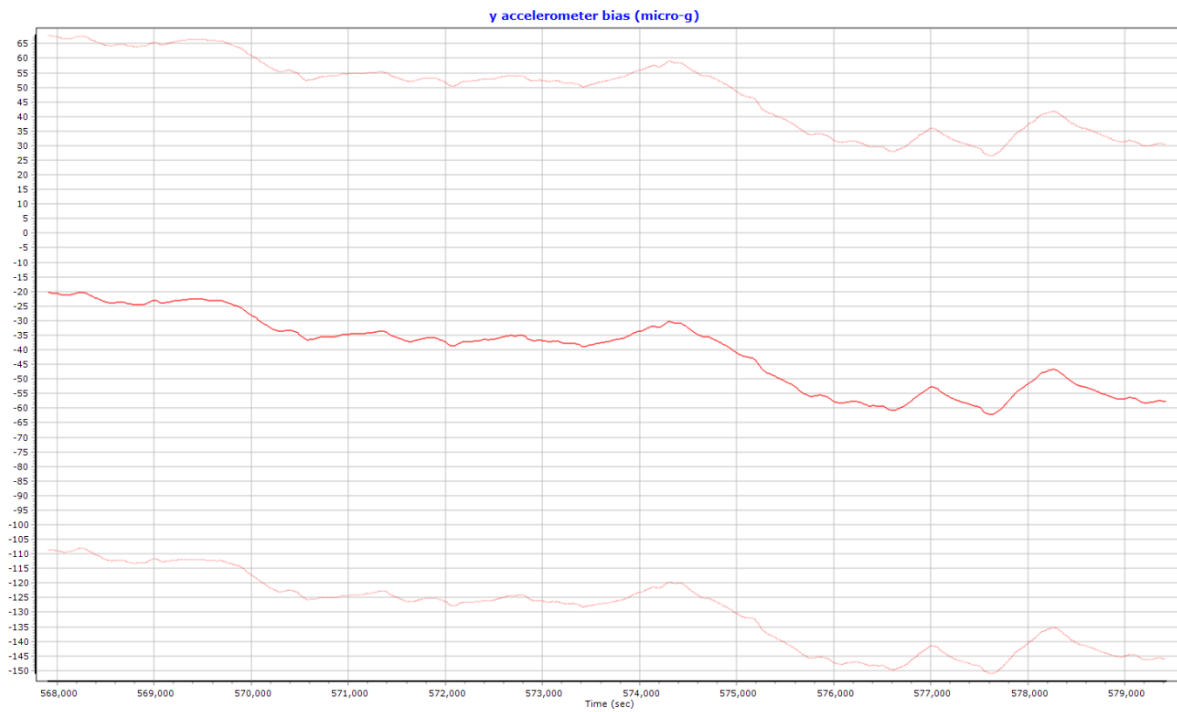
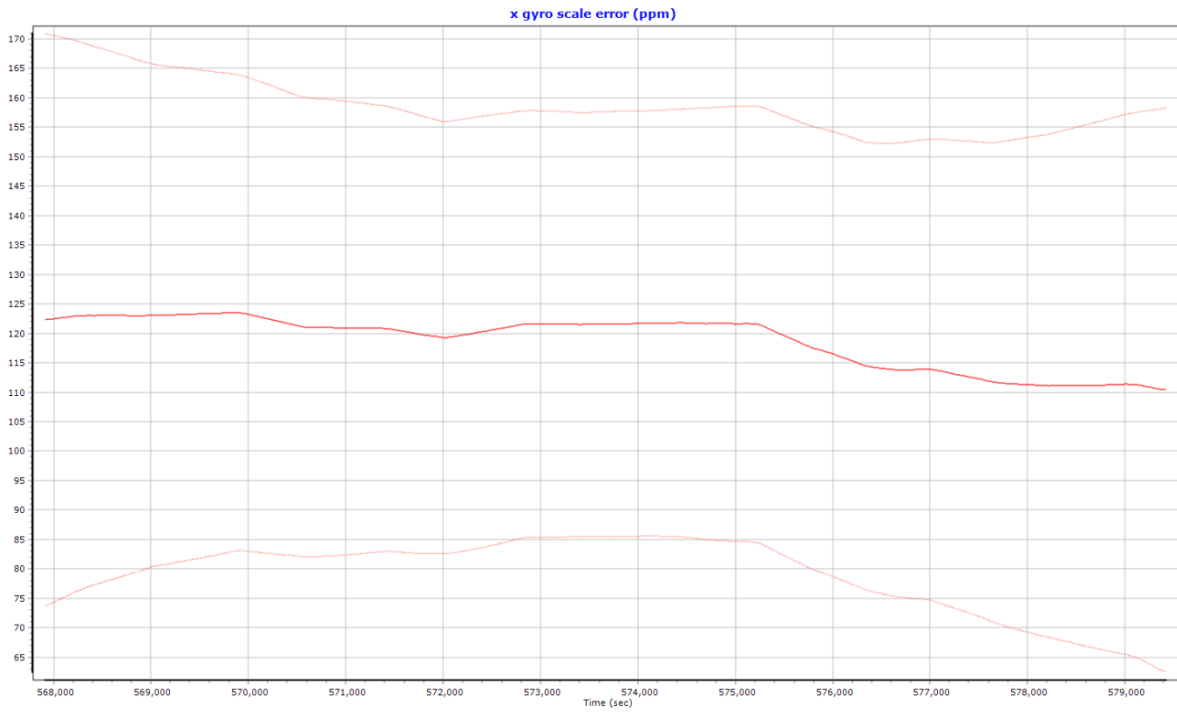
UTC Offset: 18.000

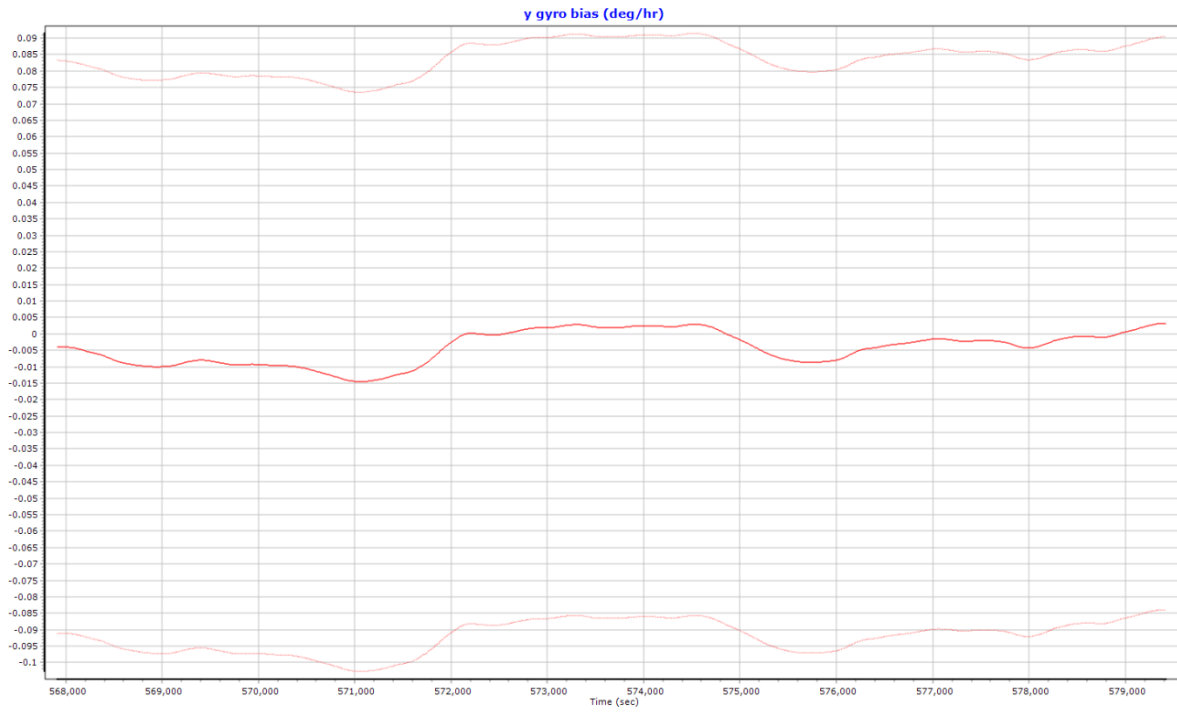
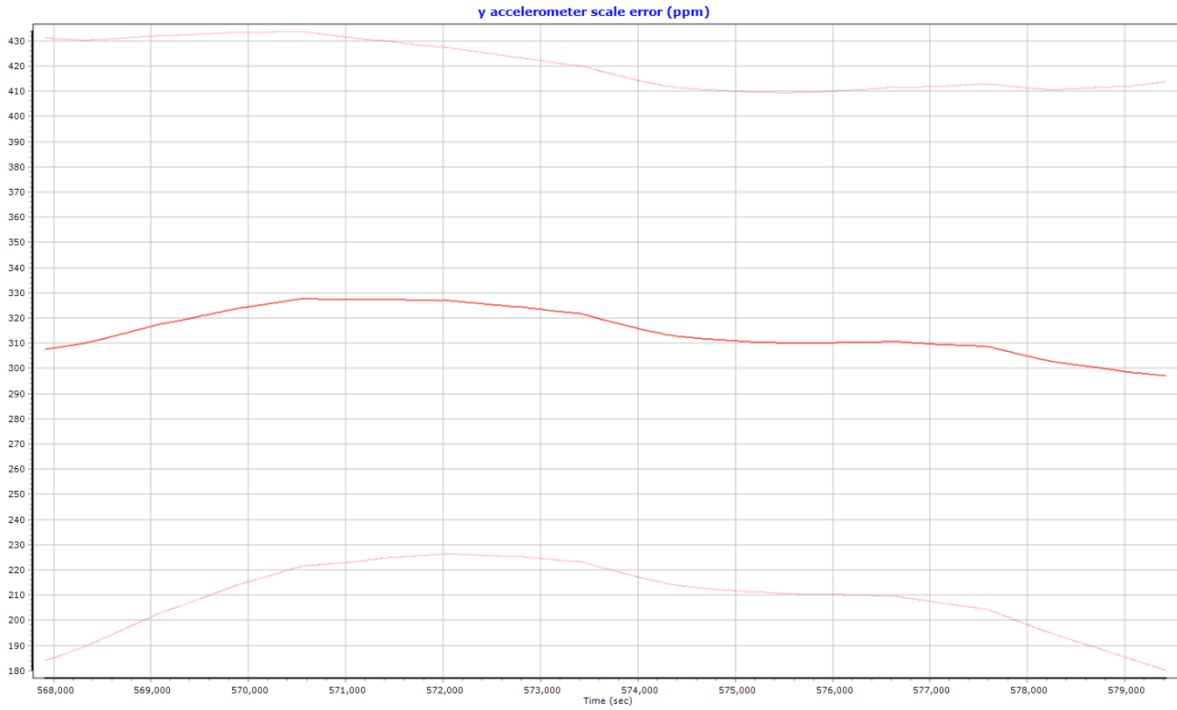
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

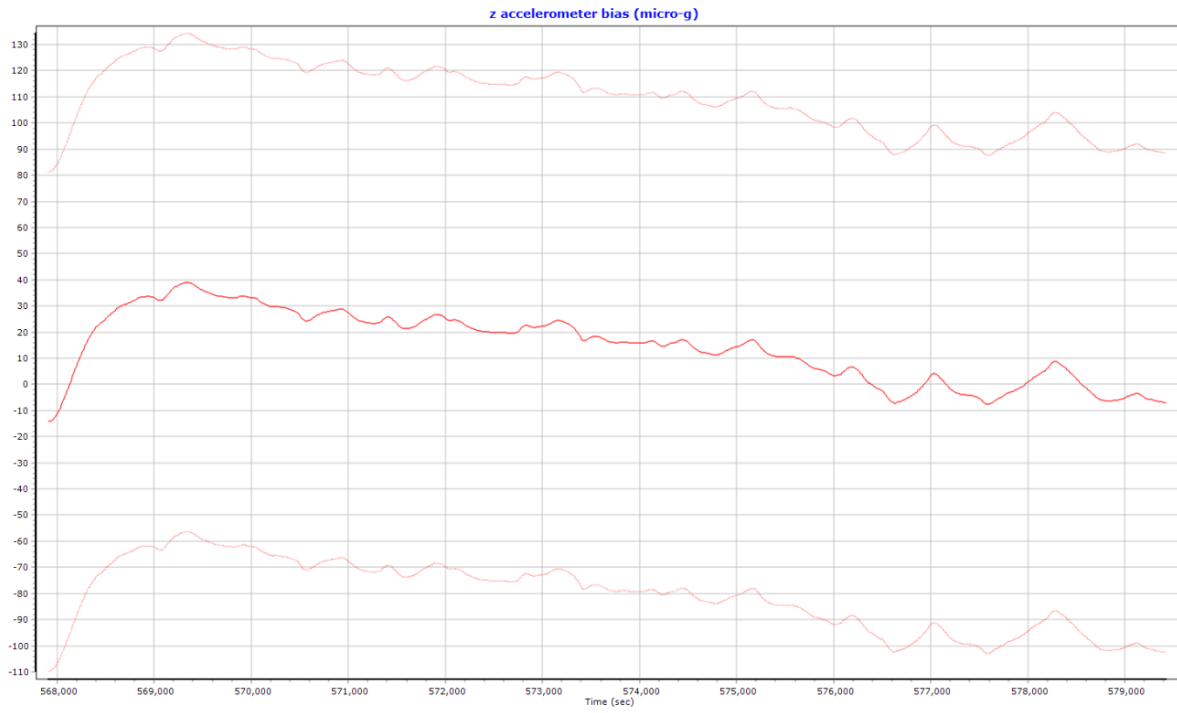
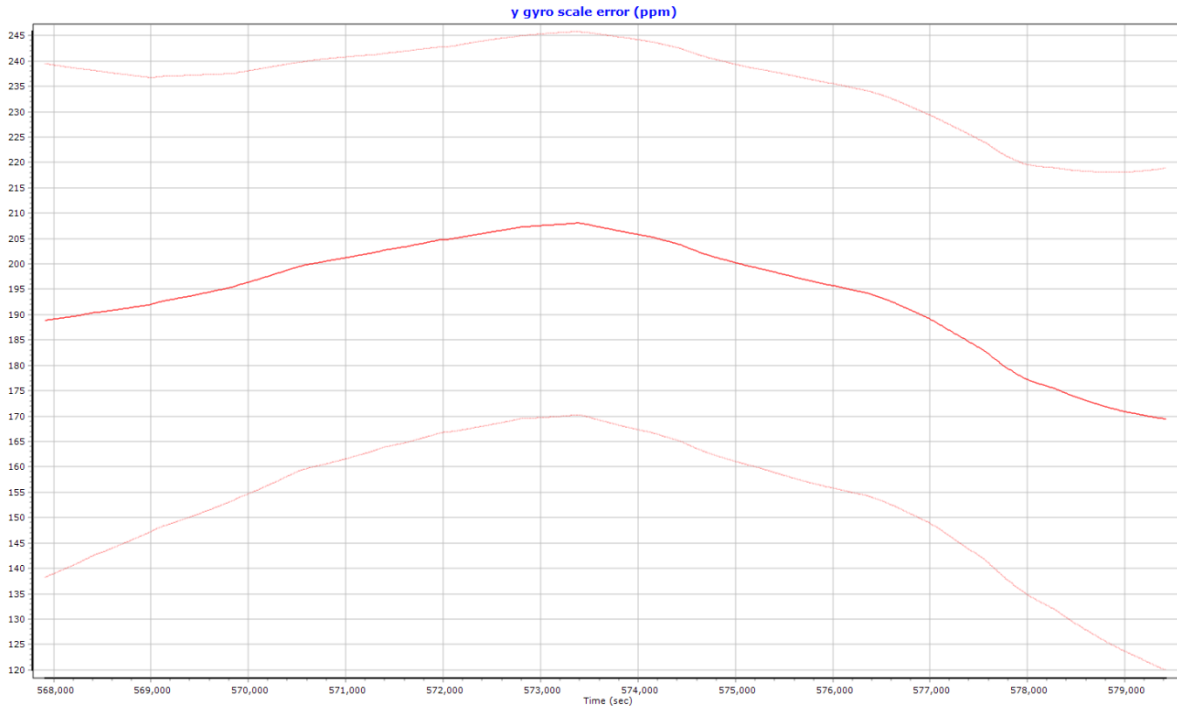
OK Cancel

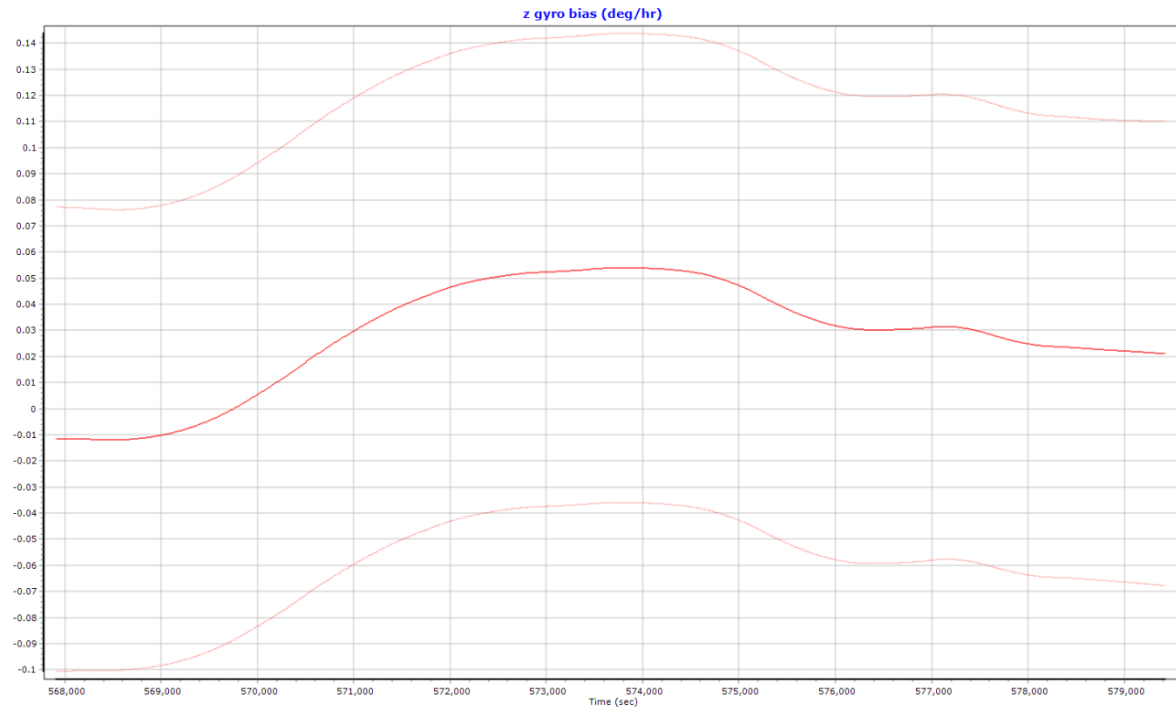
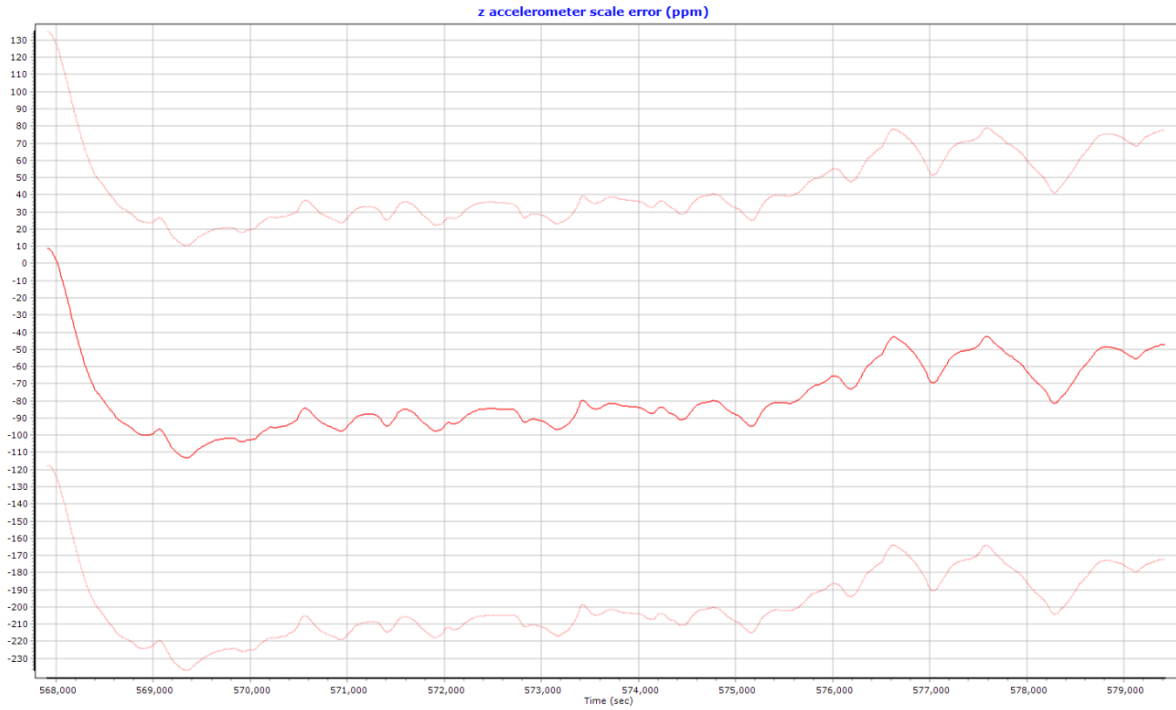


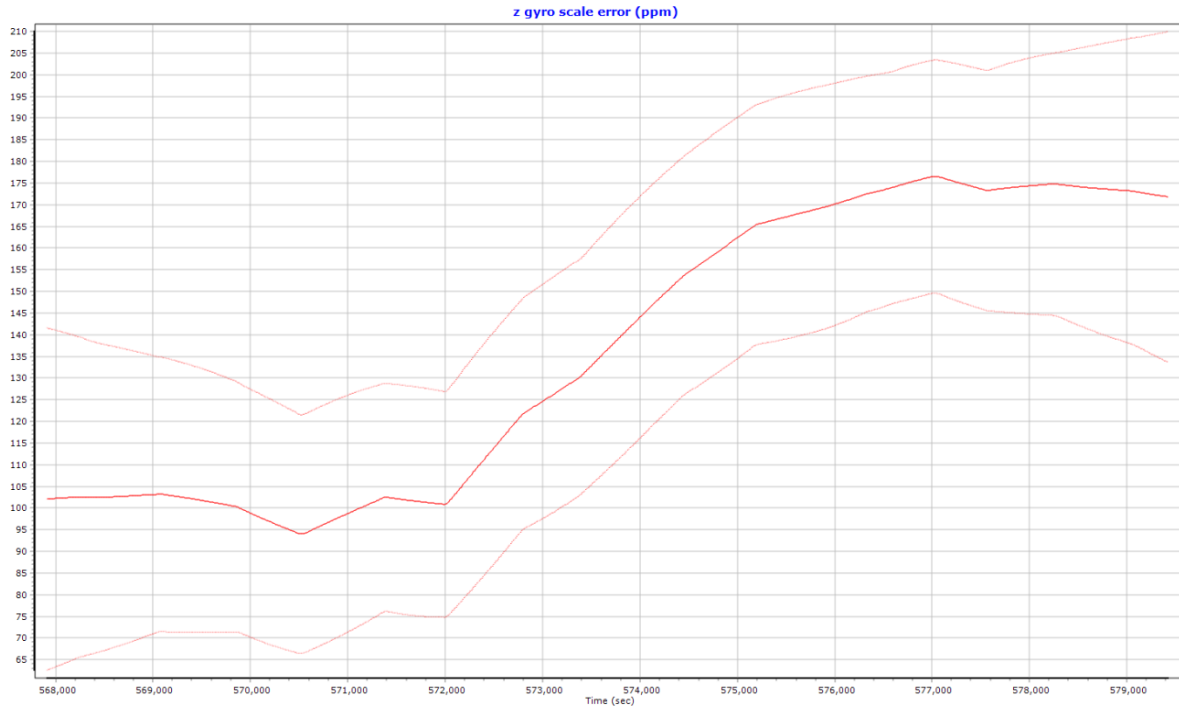




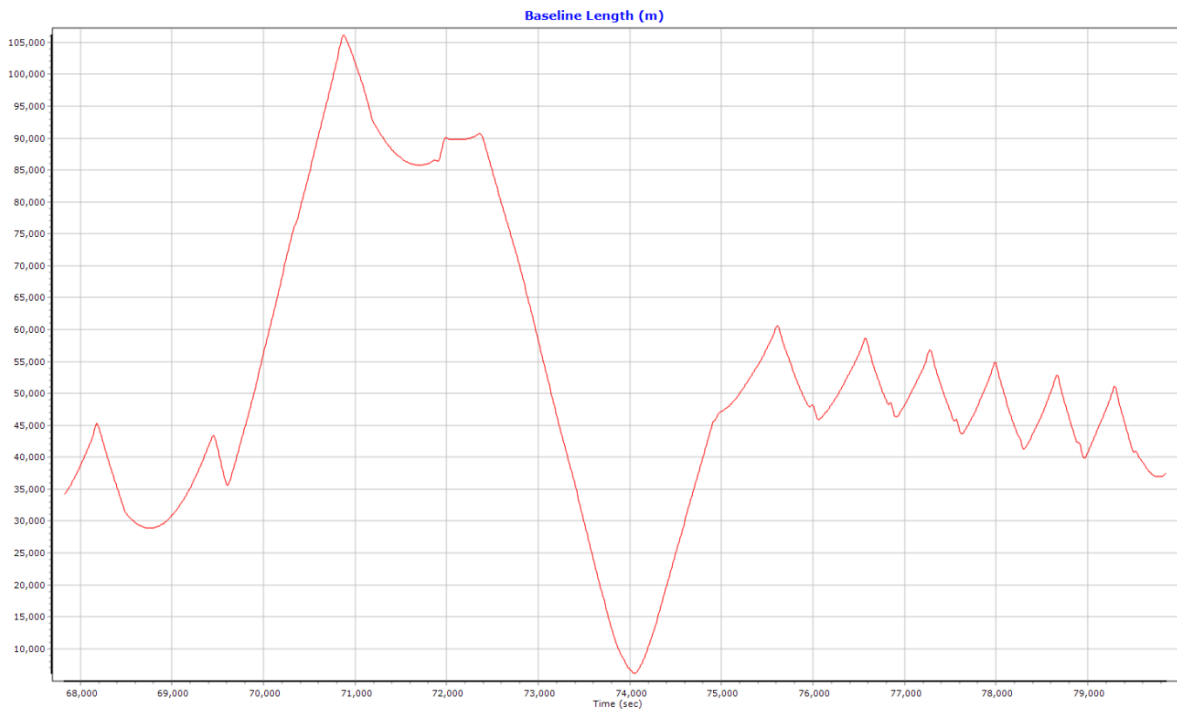


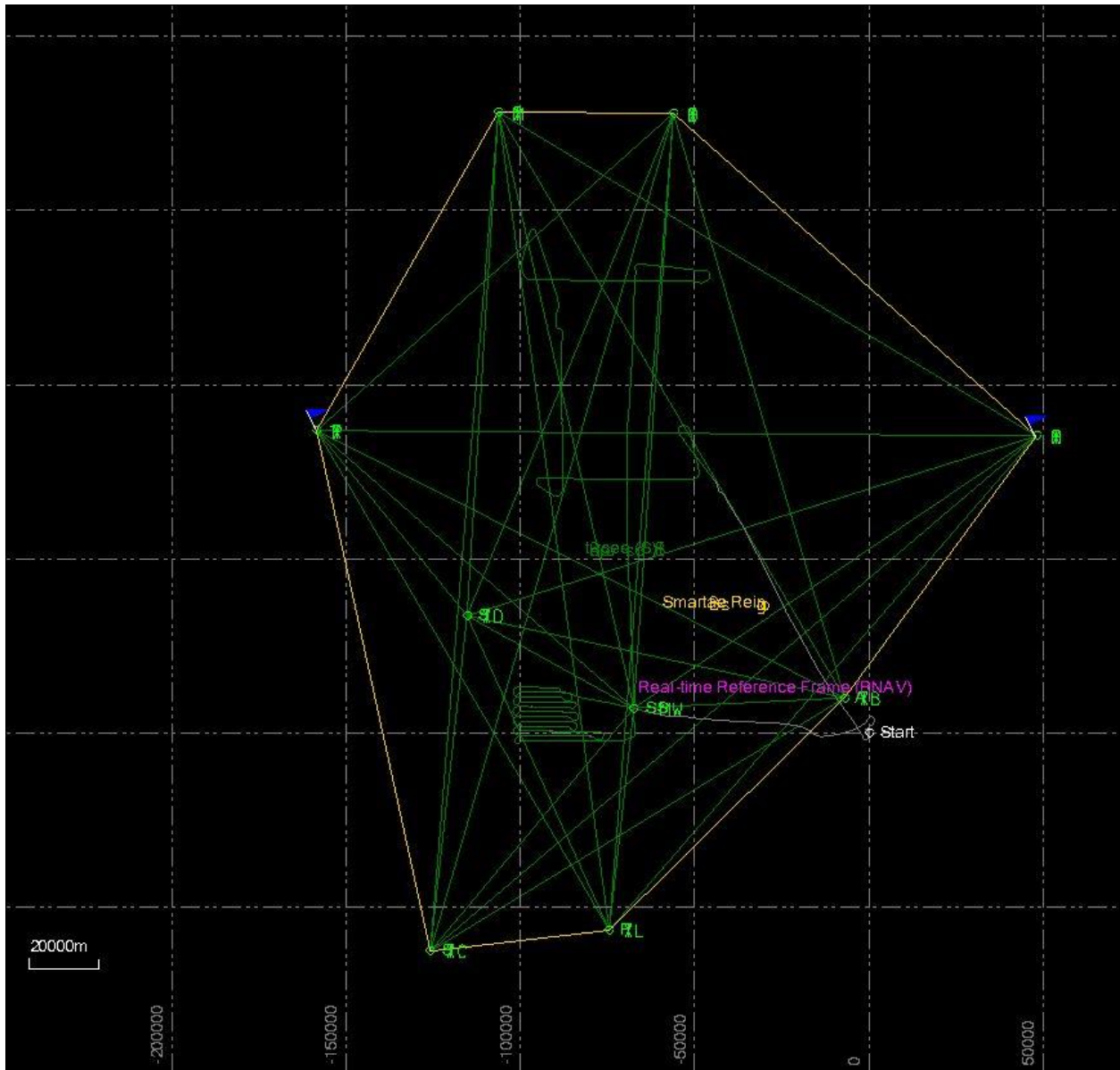


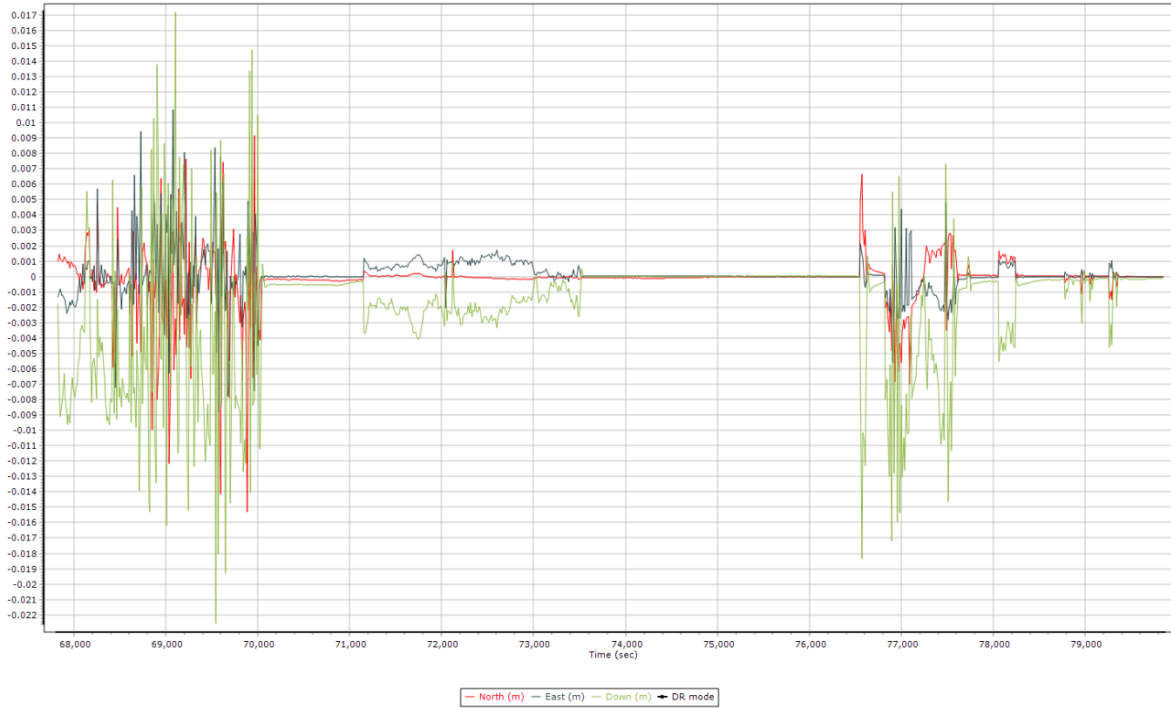




RBV18077A







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:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

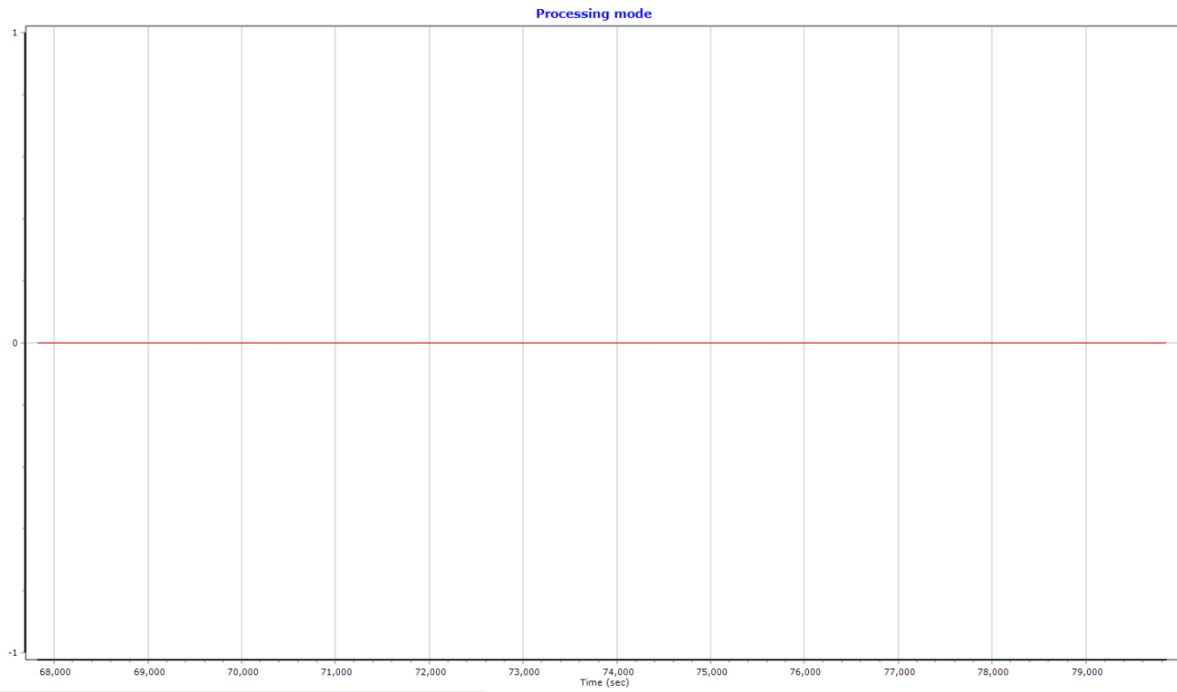
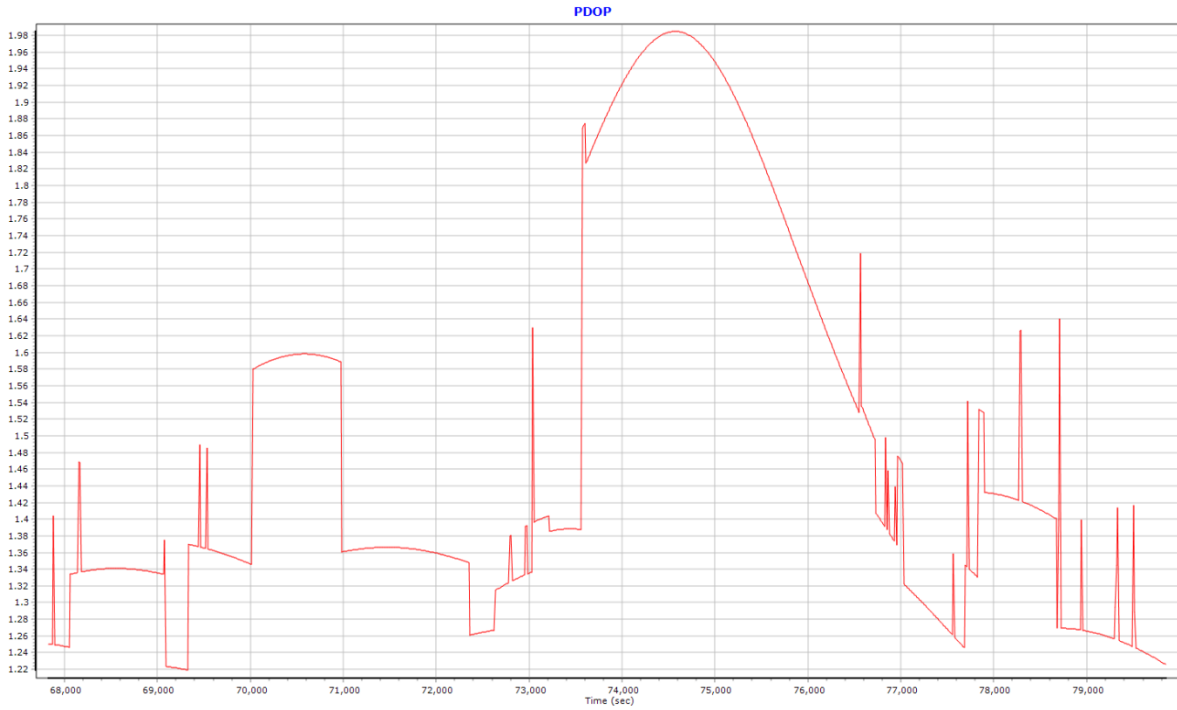
Aircraft to Stabilized Mount Mounting Angles

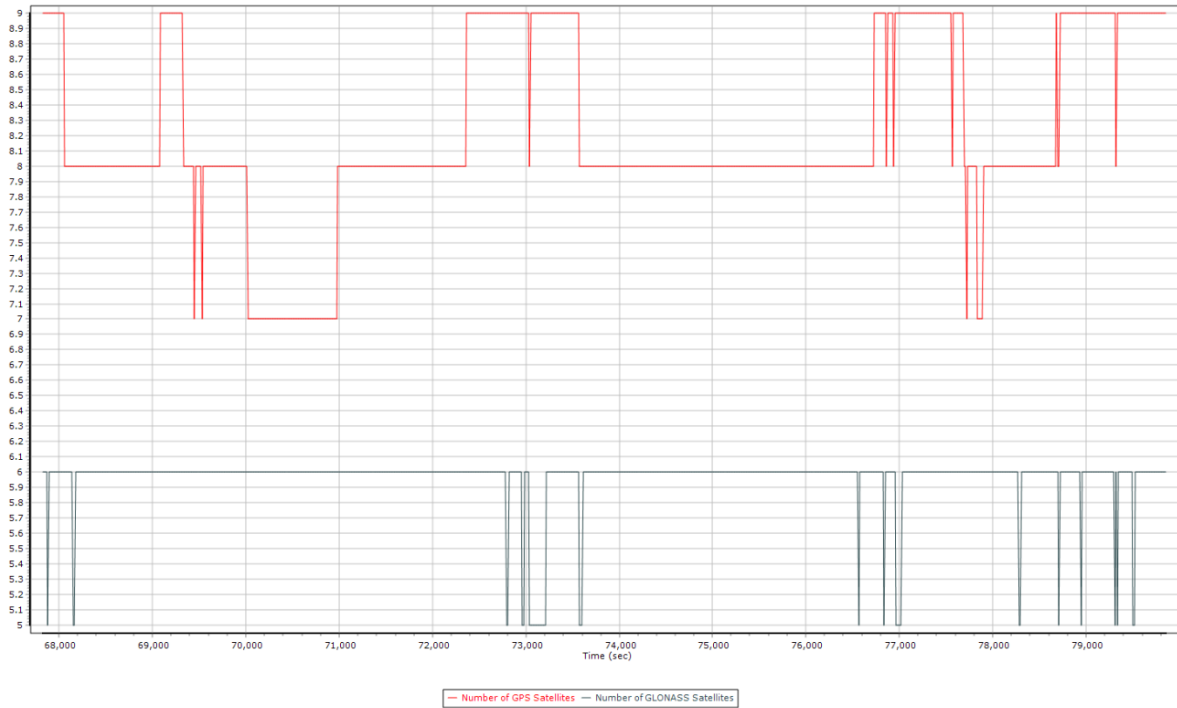
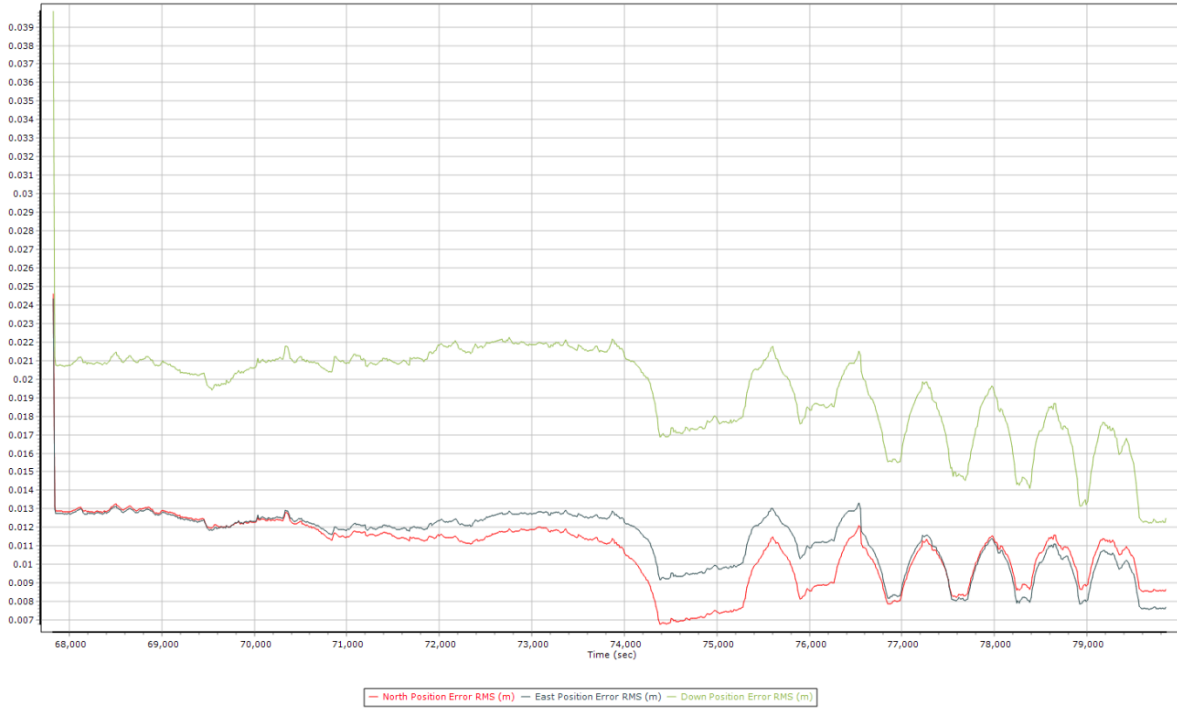
X:

Y:

Z:

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





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

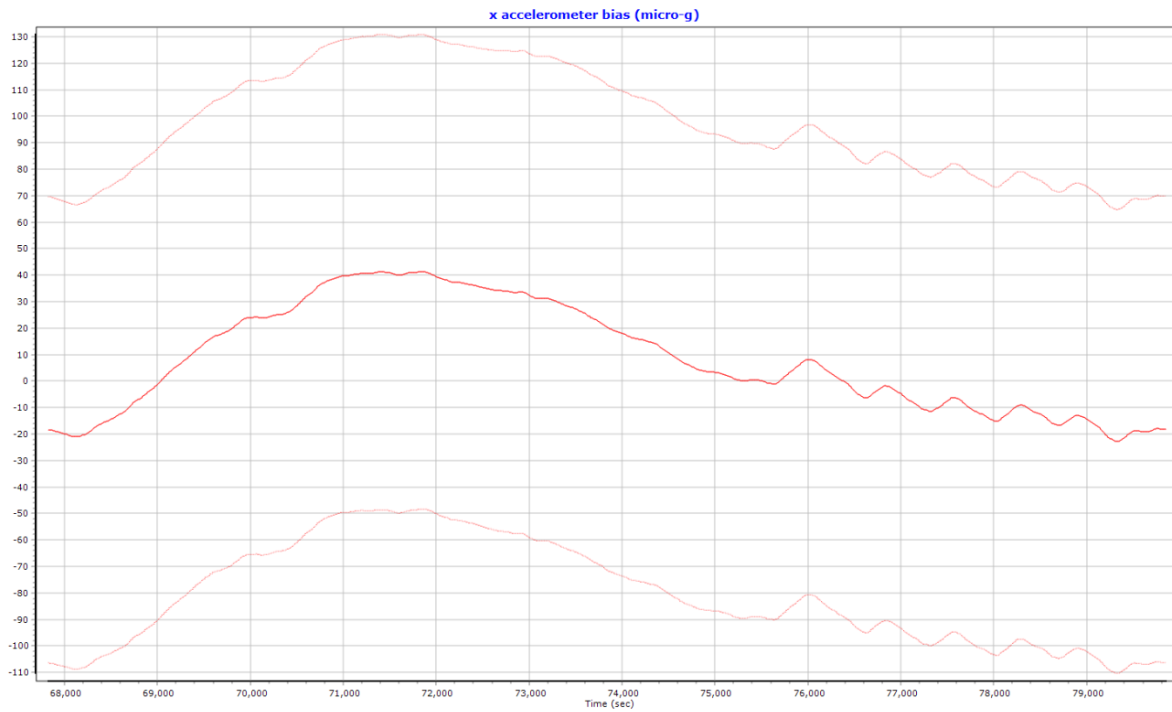
Start: 70900.000
End: 79865.156

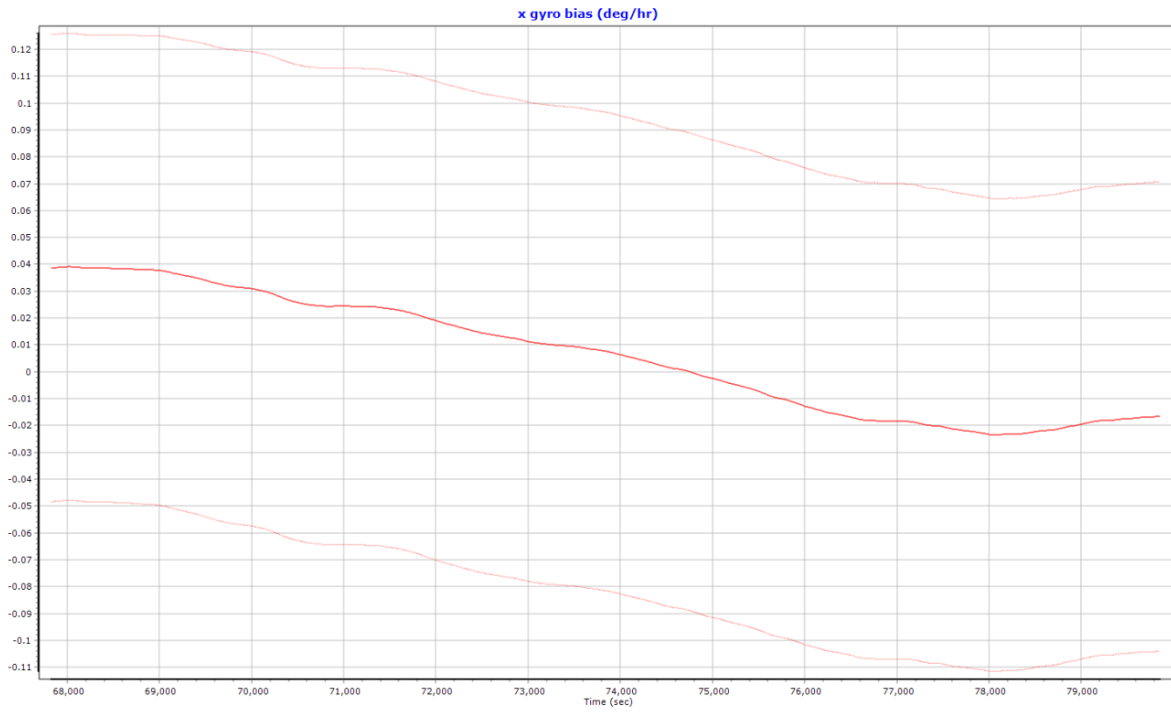
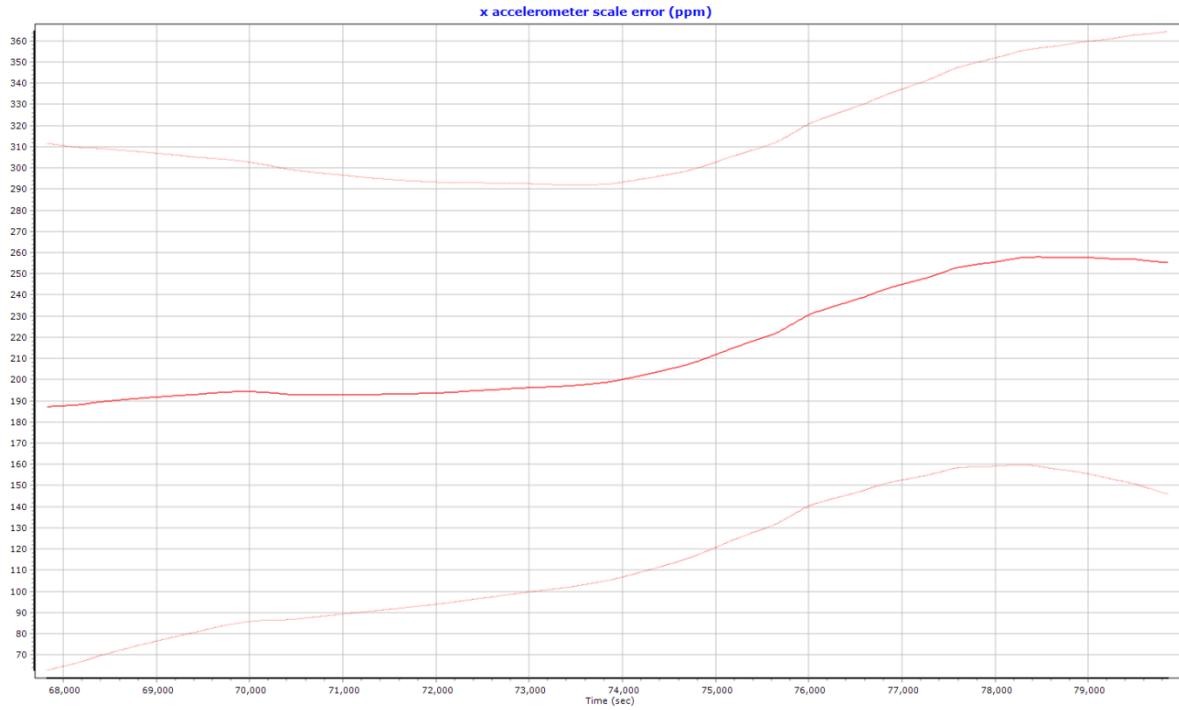
Entire time interval
 Seconds of start week

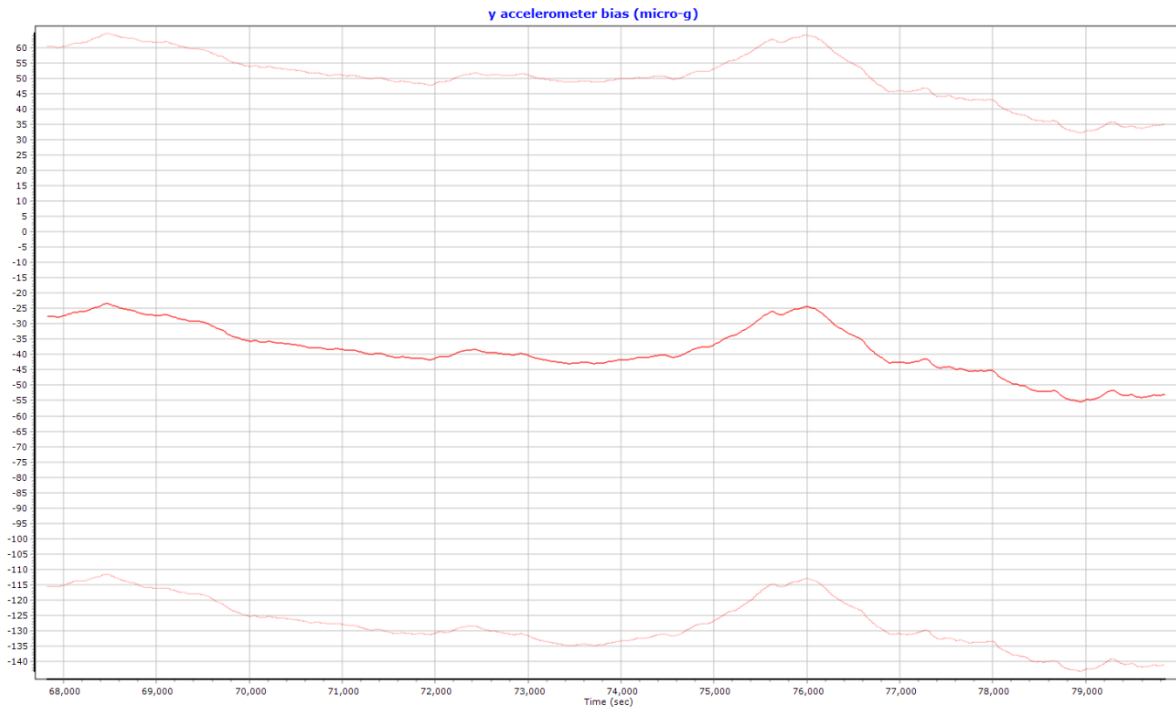
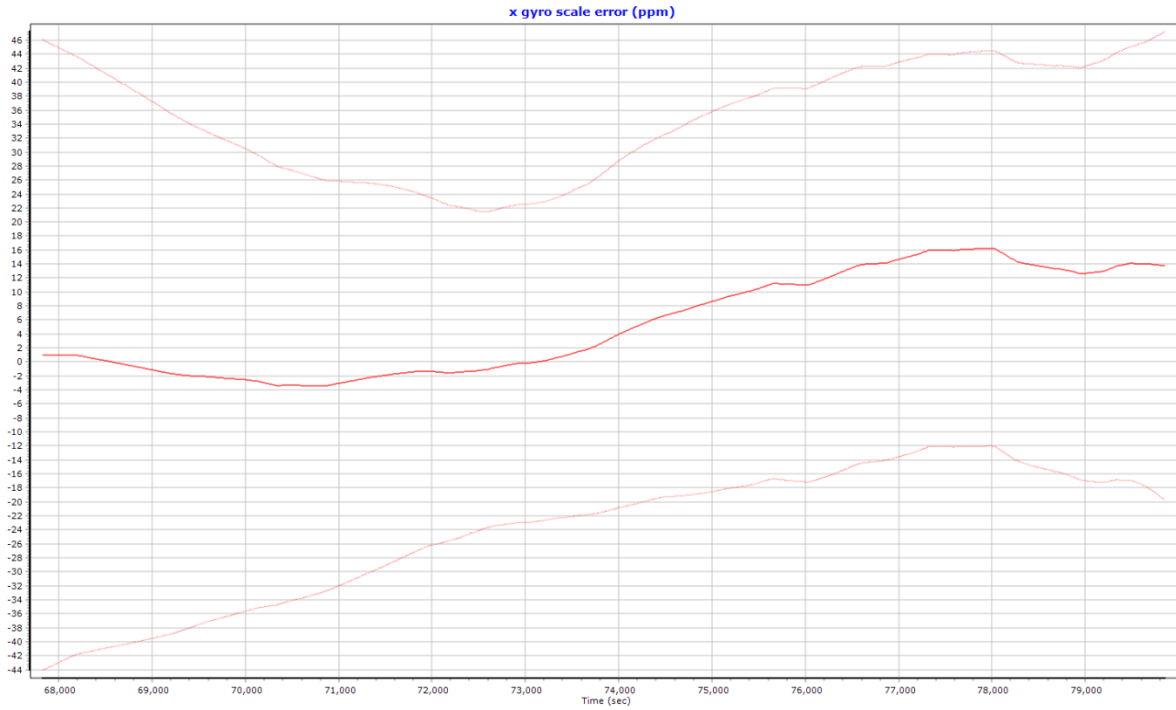
UTC Offset: 18.000

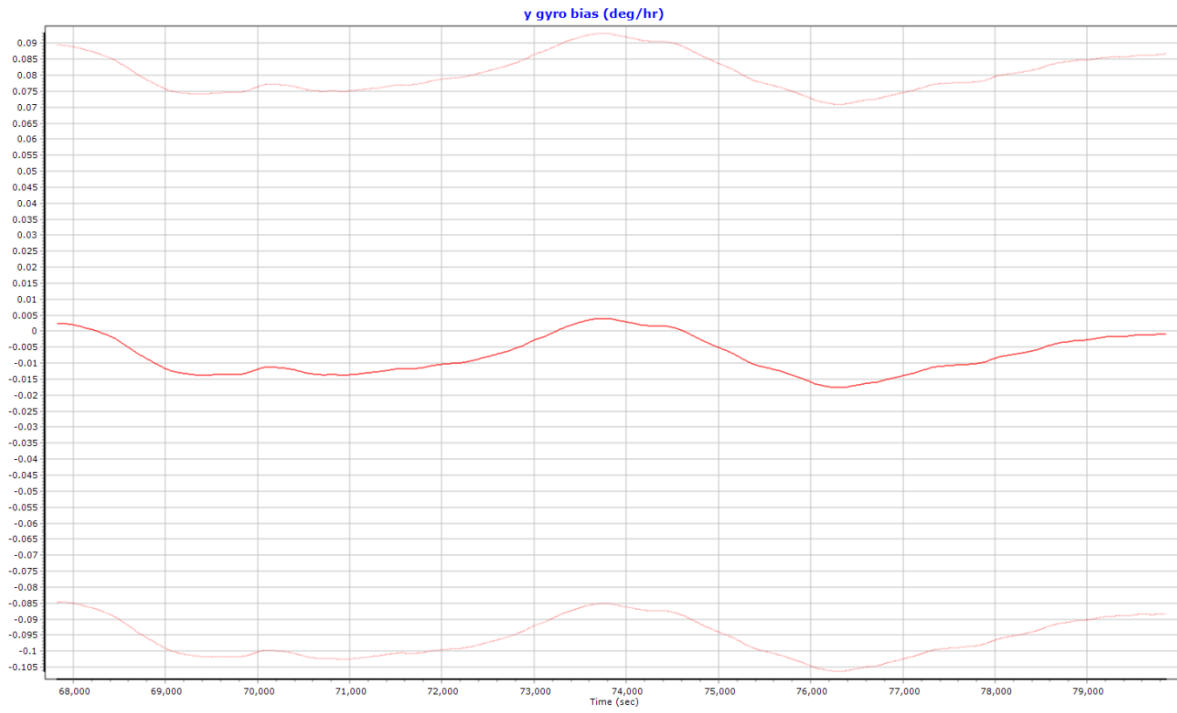
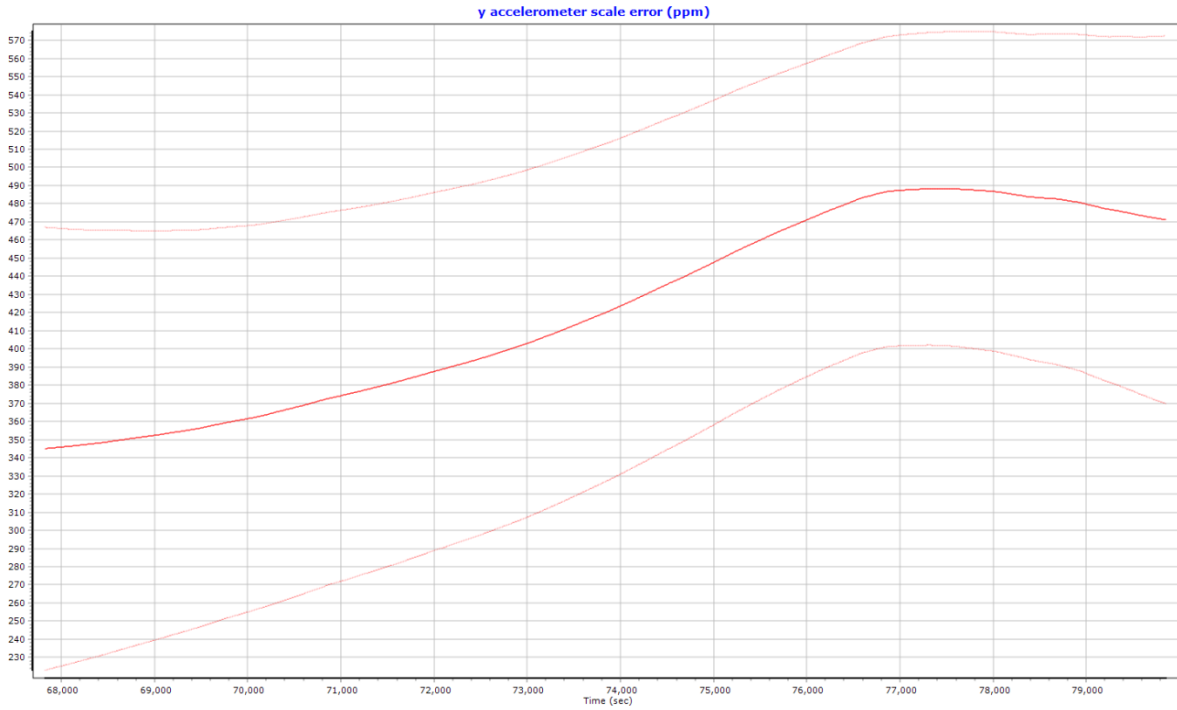
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

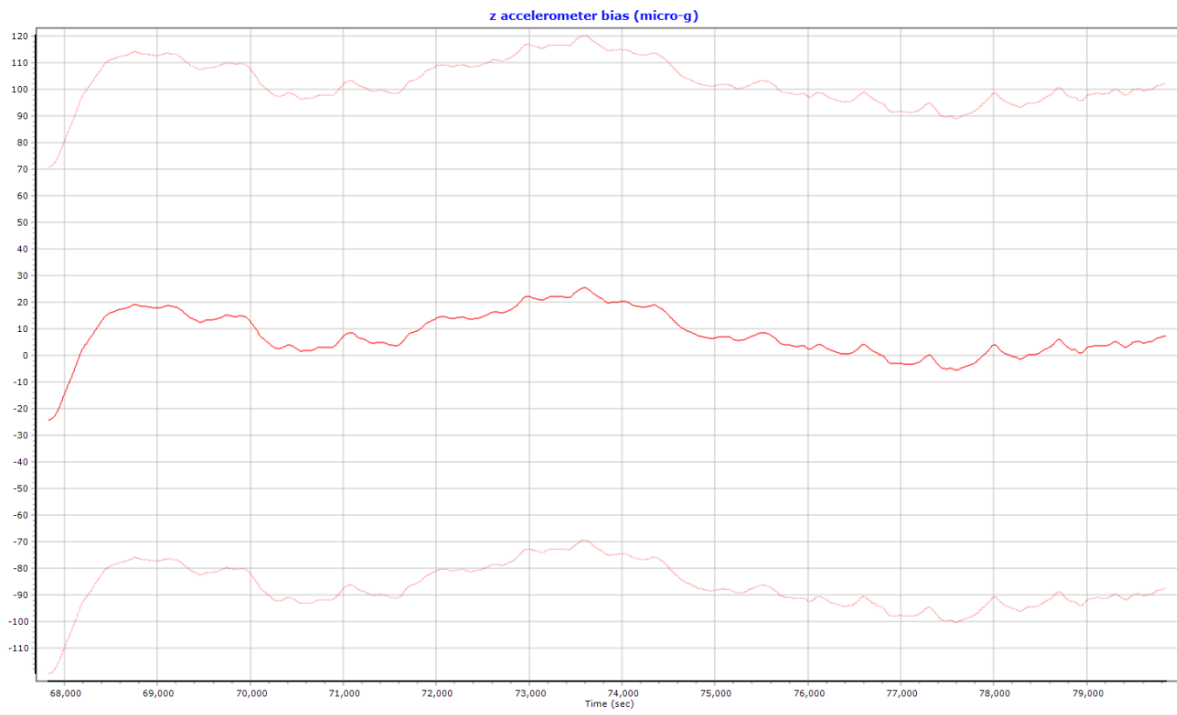
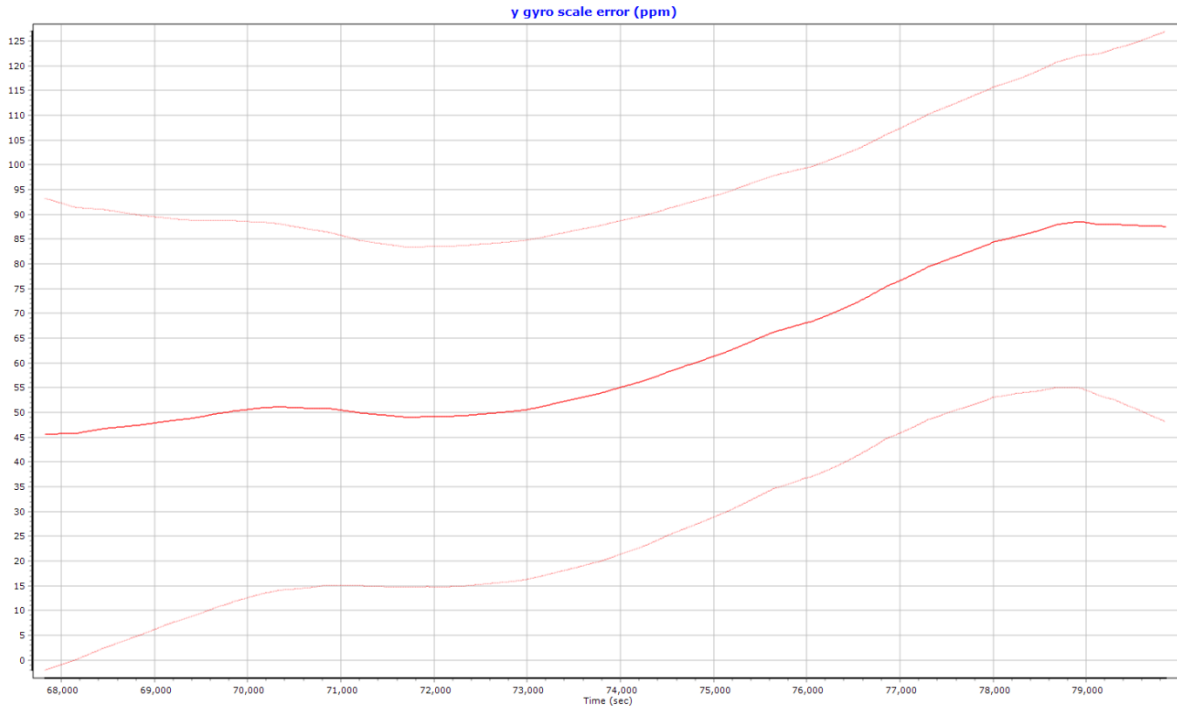
OK Cancel

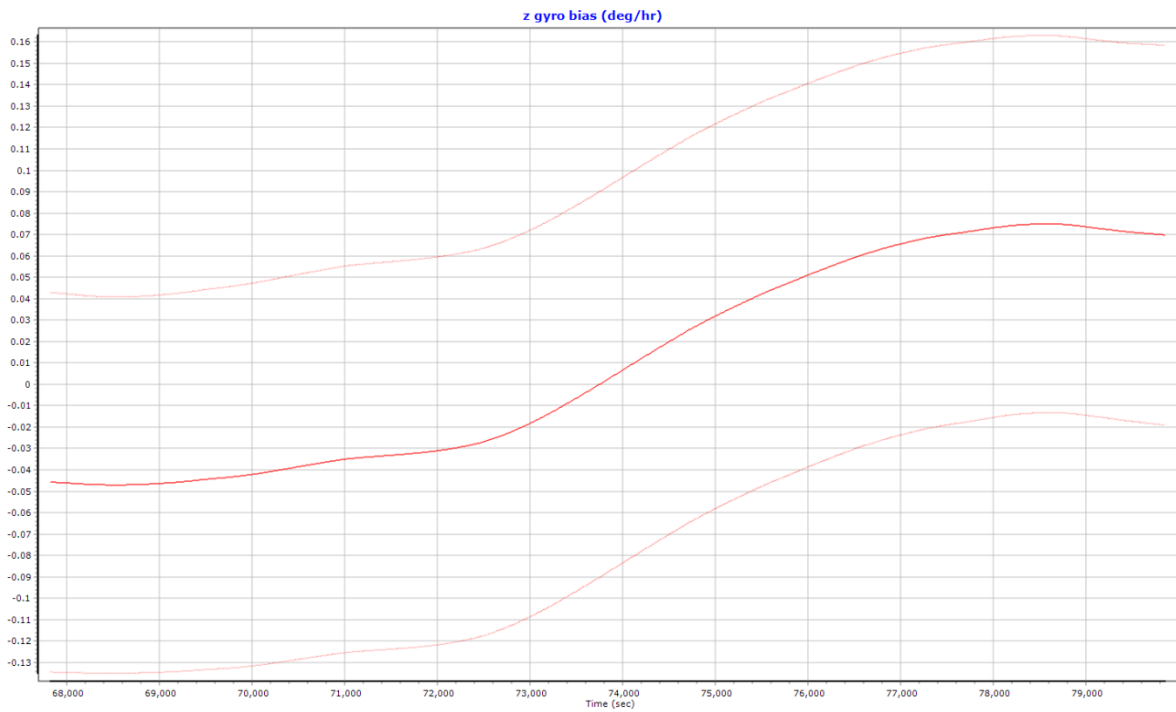
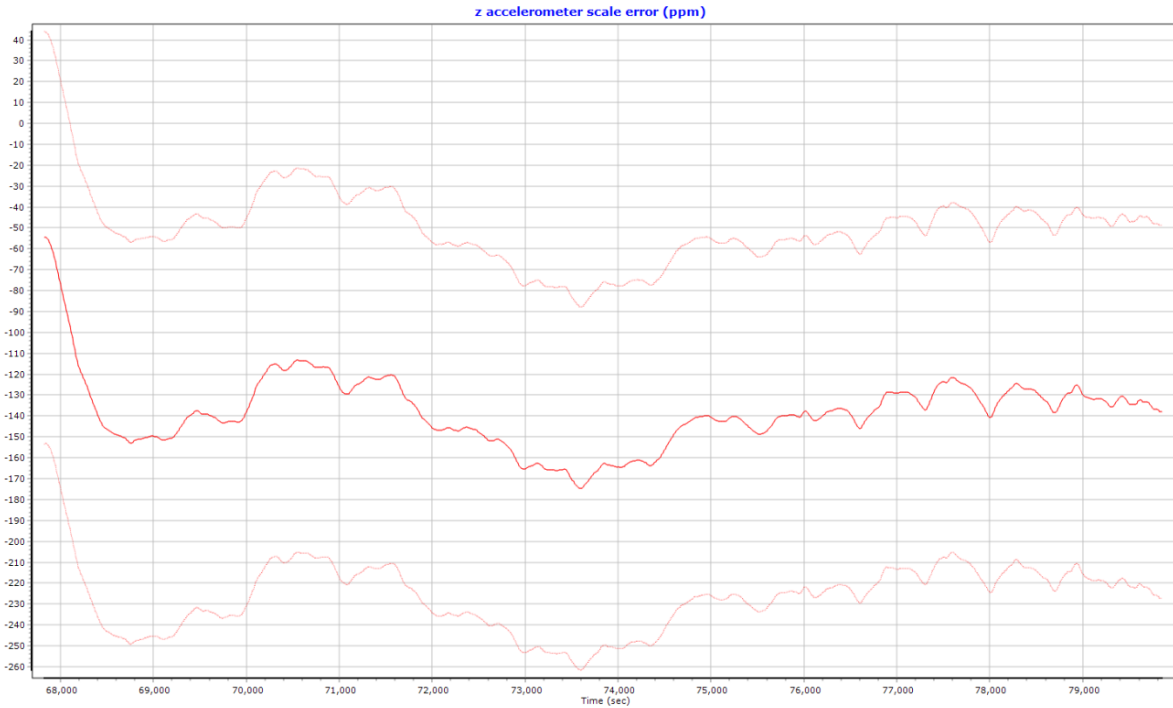


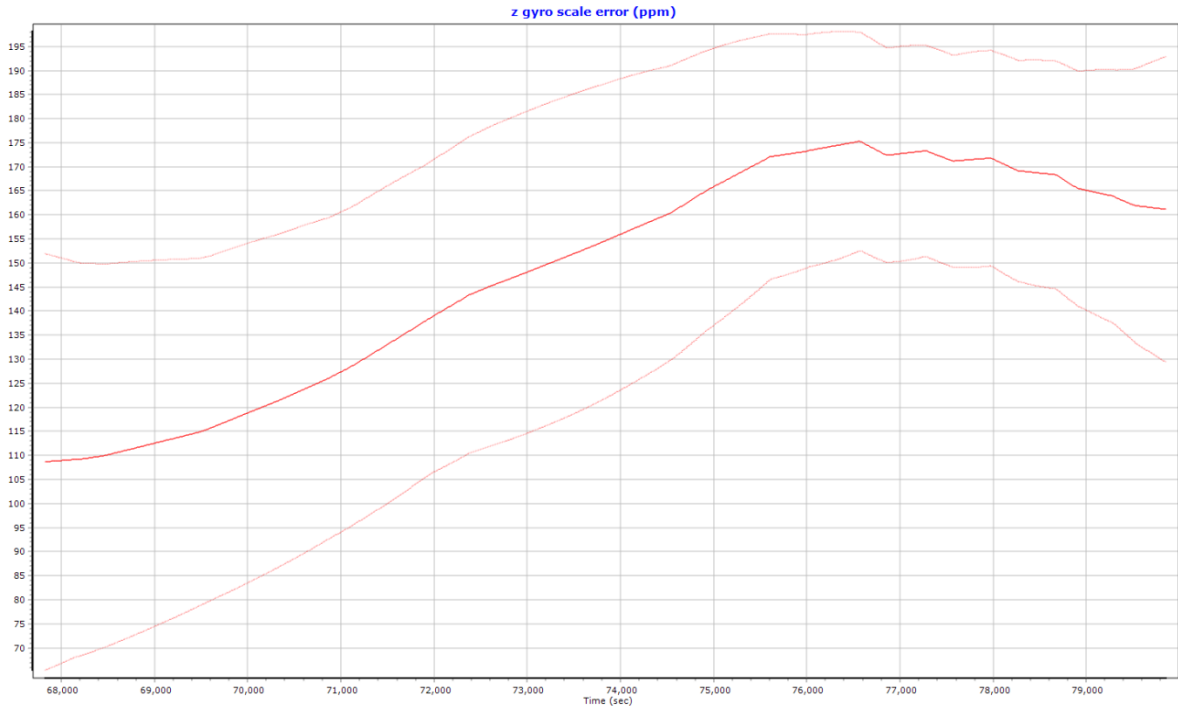




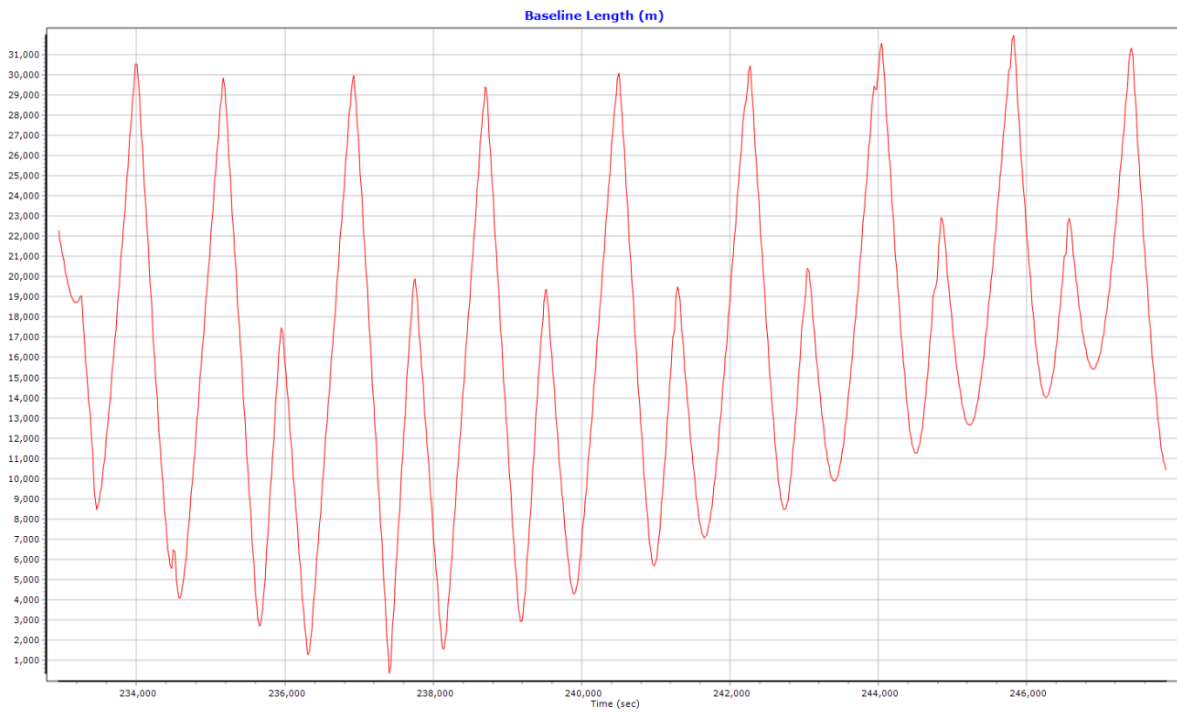
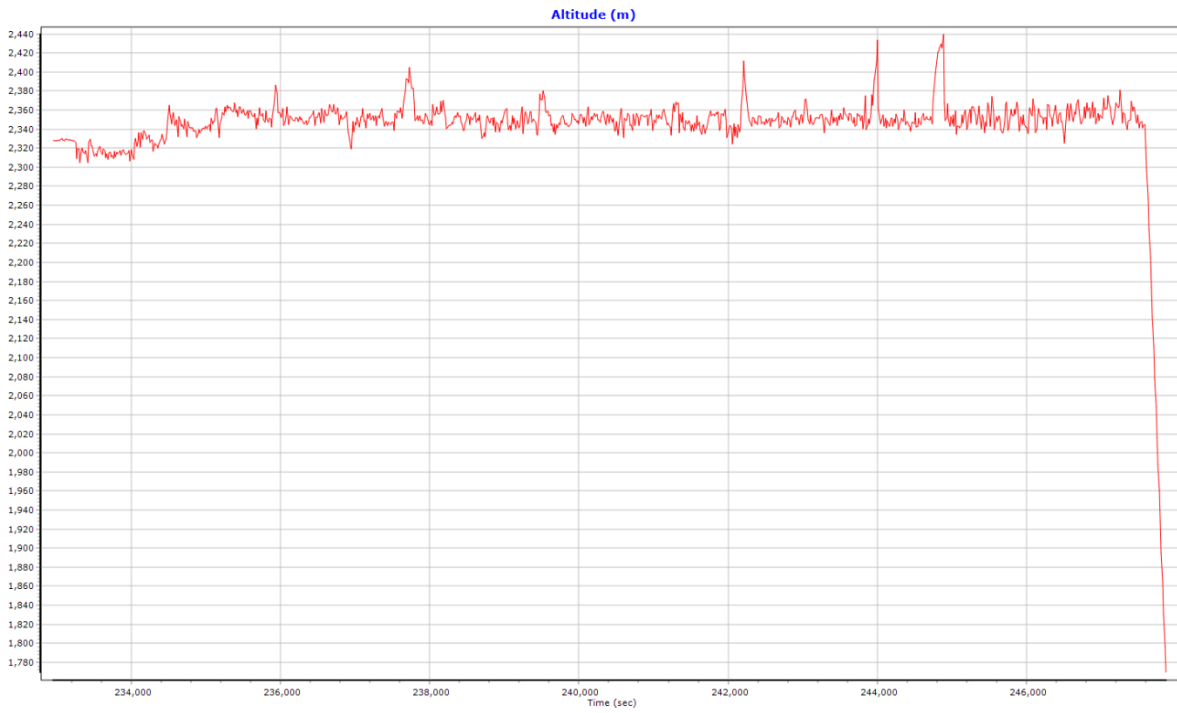


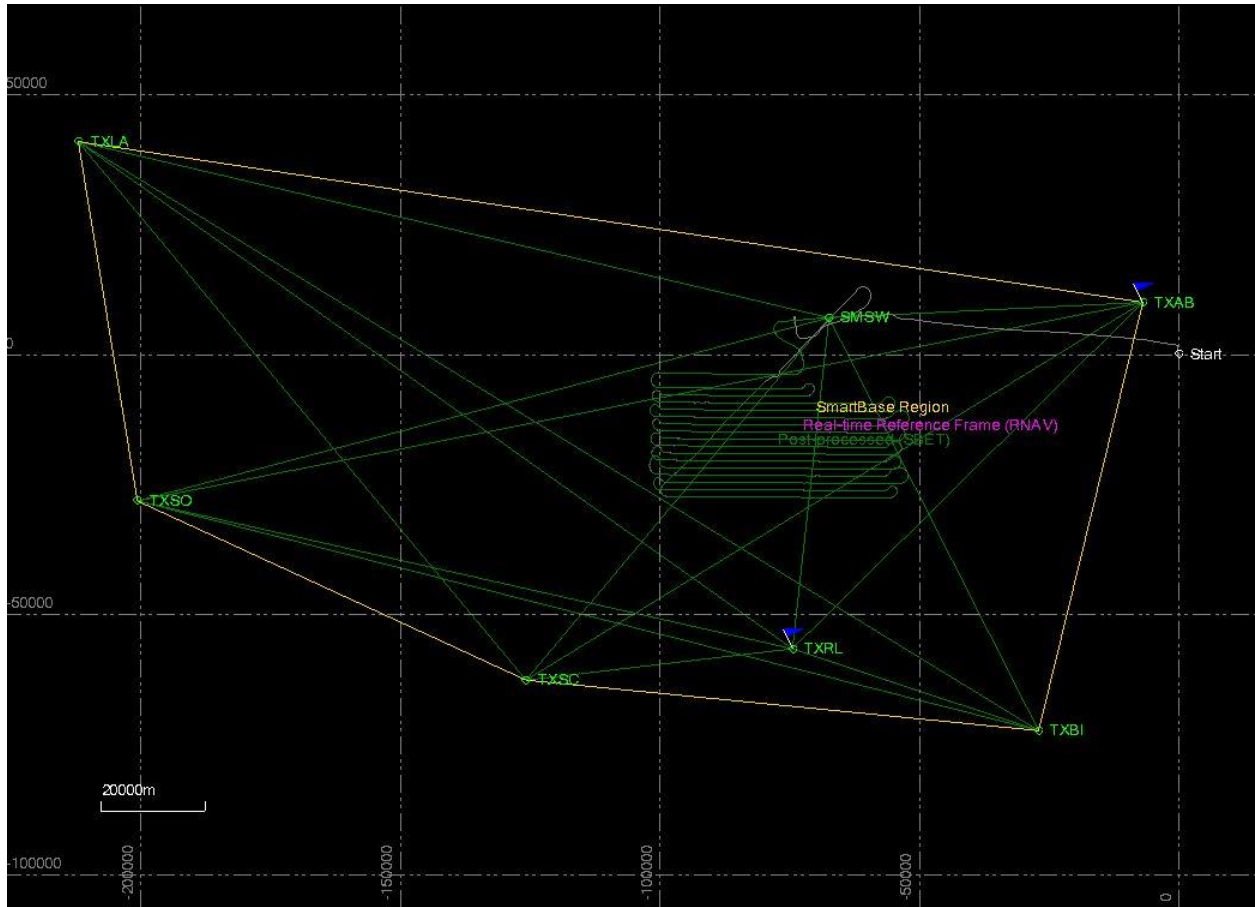






RBV18079A





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 Primary GNSS Lever Arm

X: -0.065 m

Y: 0.014 m

Z: -1.021 m

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

Stabilized Mount to IMU Mounting Angles

X: 0.000 deg

Y: 0.000 deg

Z: 0.000 deg

Aircraft to Stabilized Mount Mounting Angles

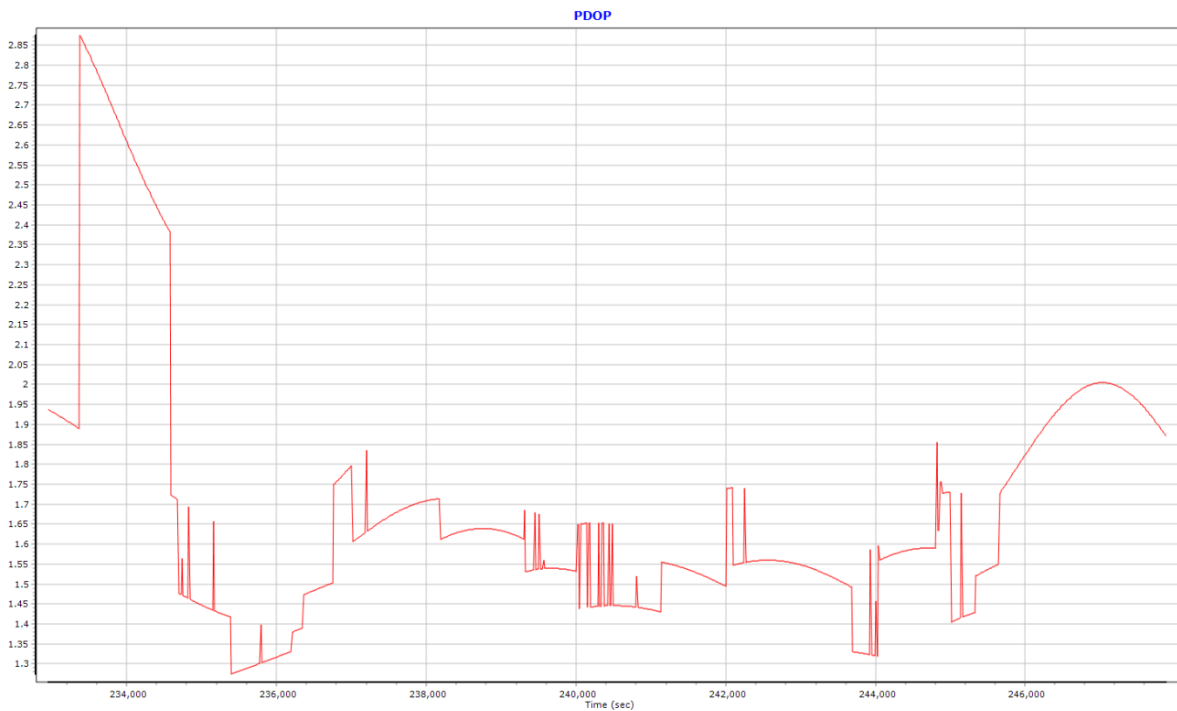
X: 0.000 deg

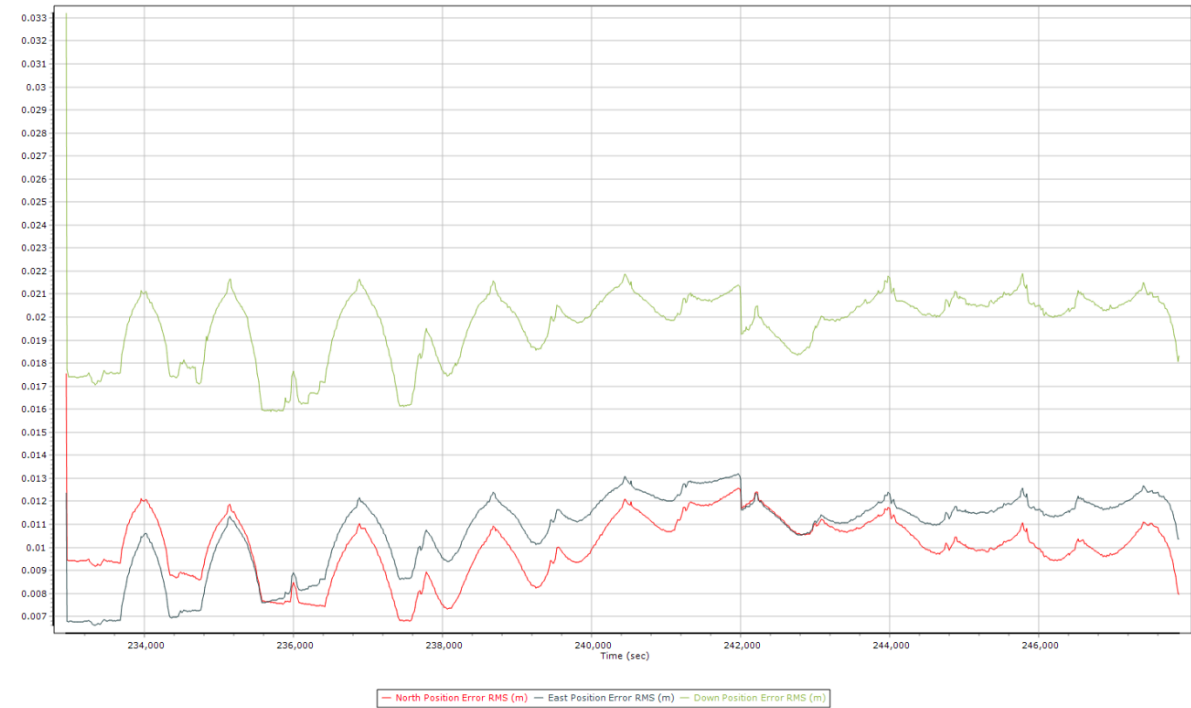
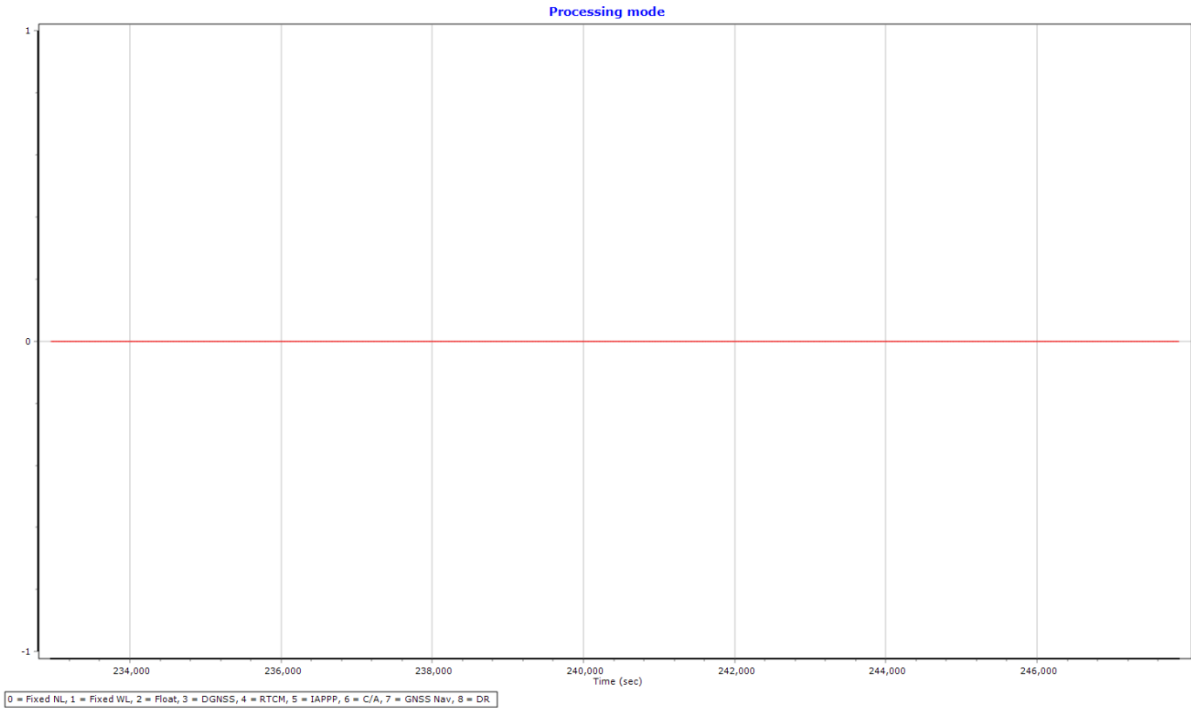
Y: 0.000 deg

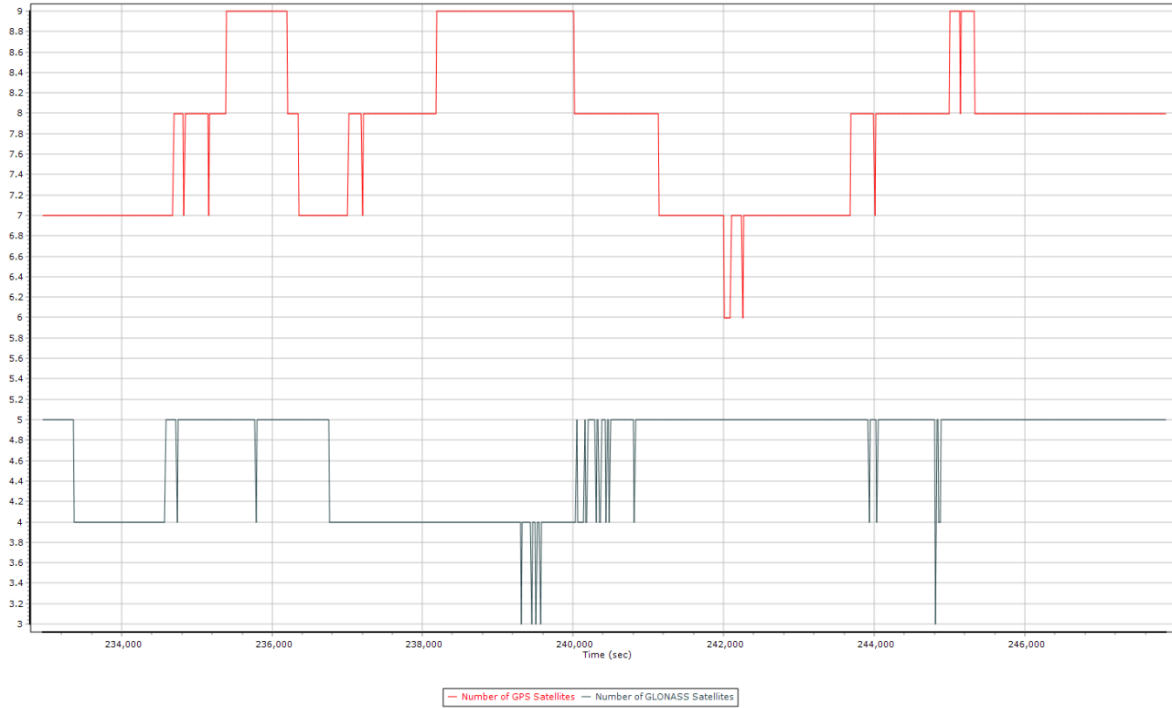
Z: 0.000 deg

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

OK Cancel







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

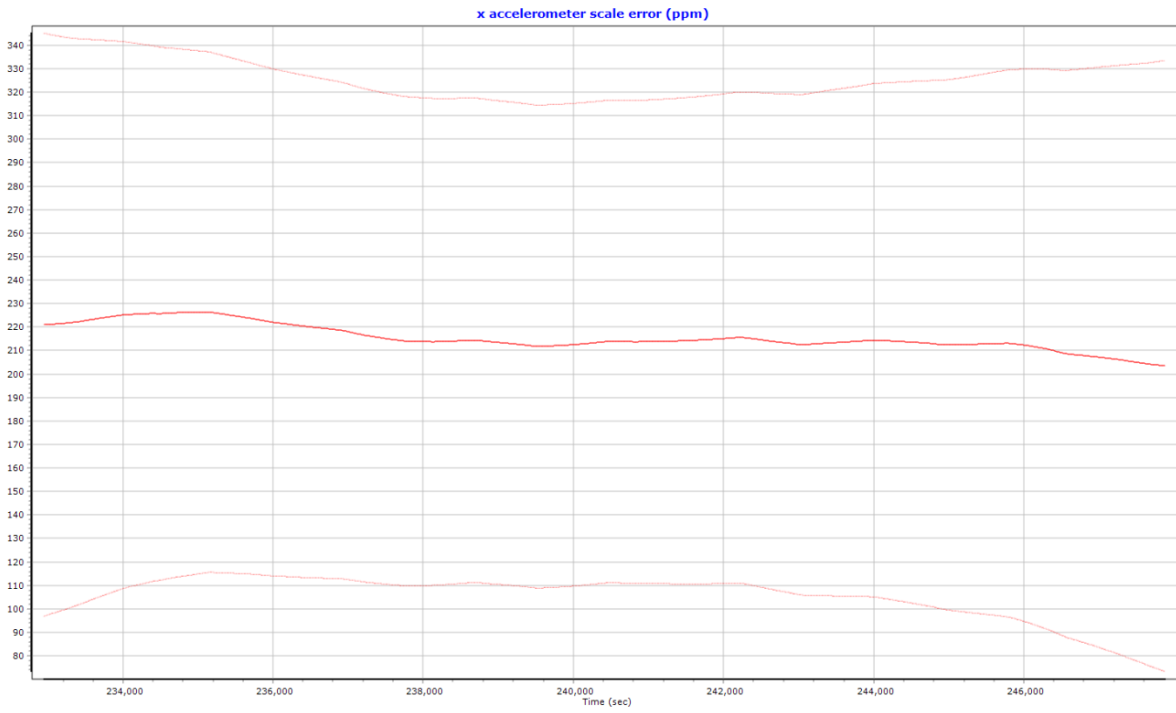
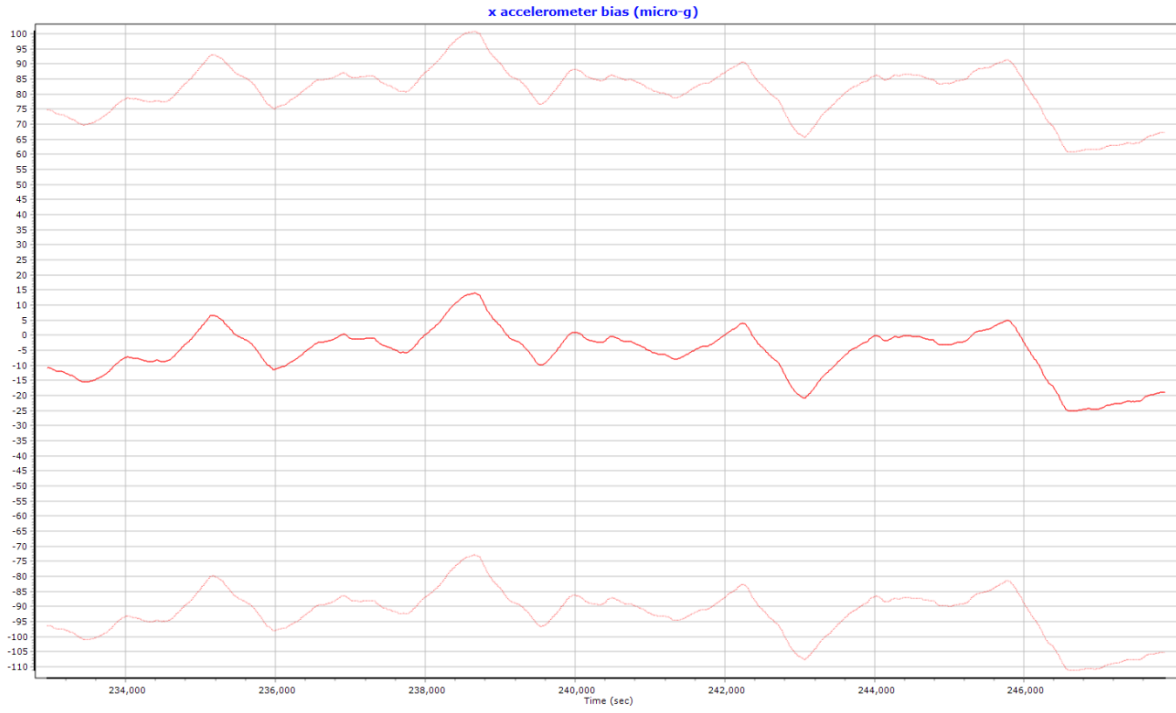
Start: 232950.395
 End: 247893.833

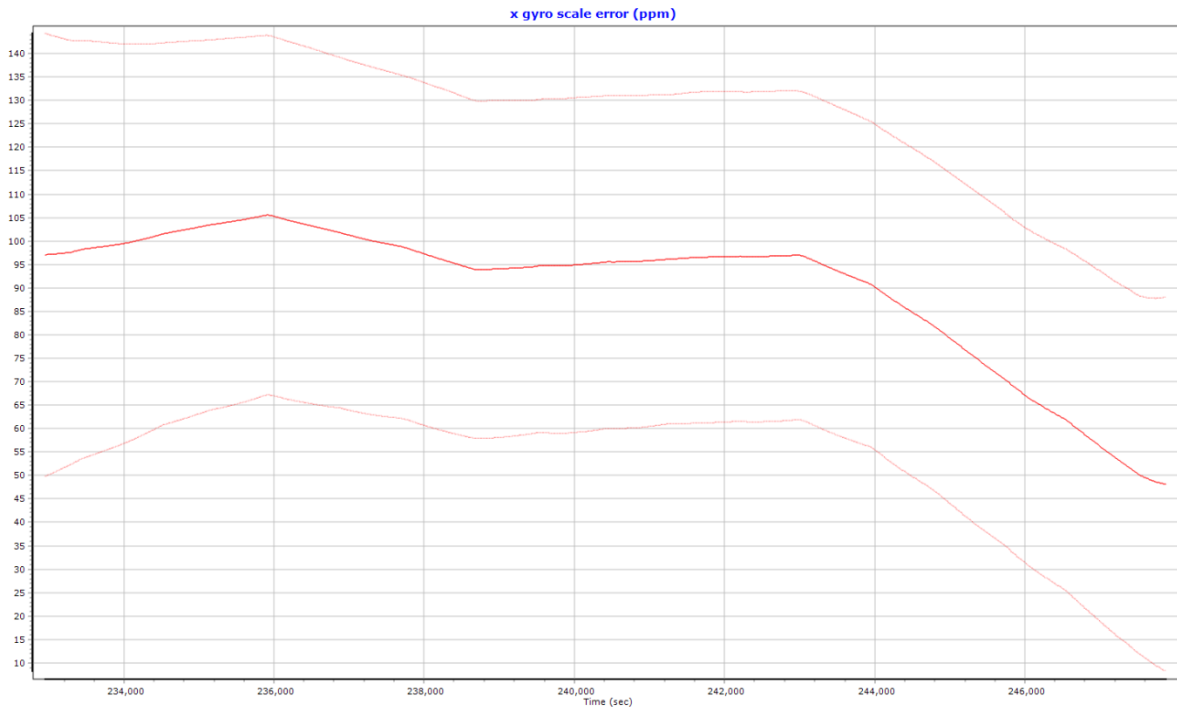
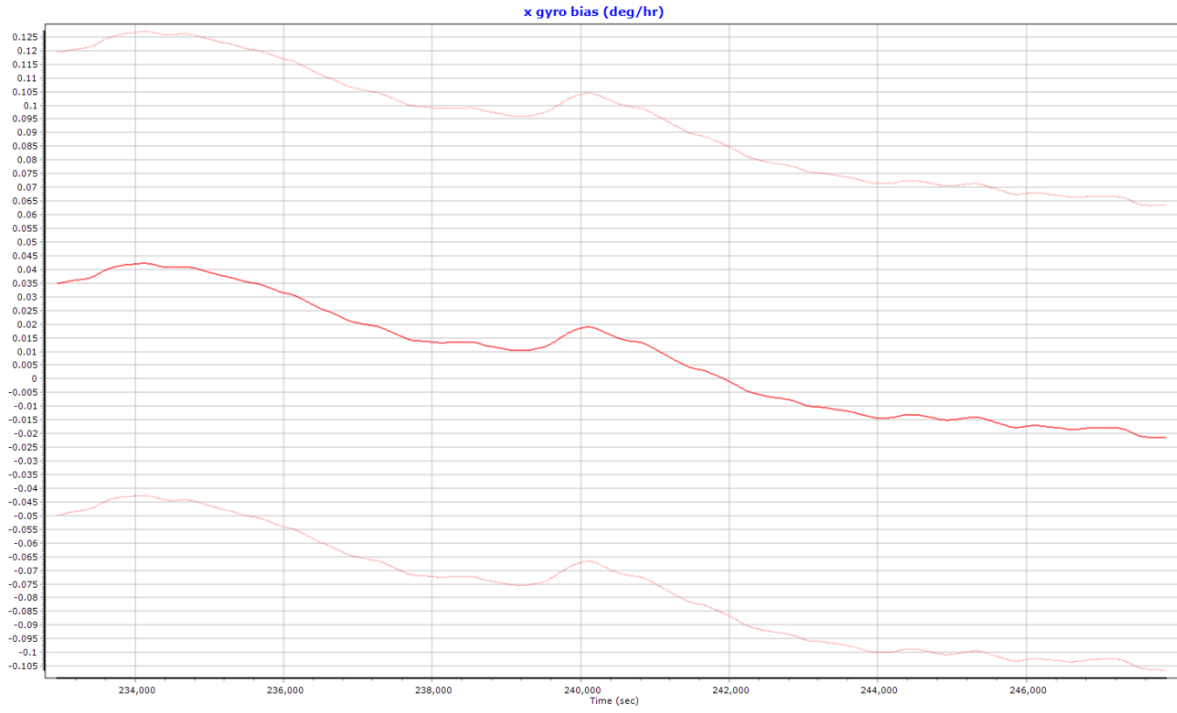
Entire time interval
 Seconds of start week

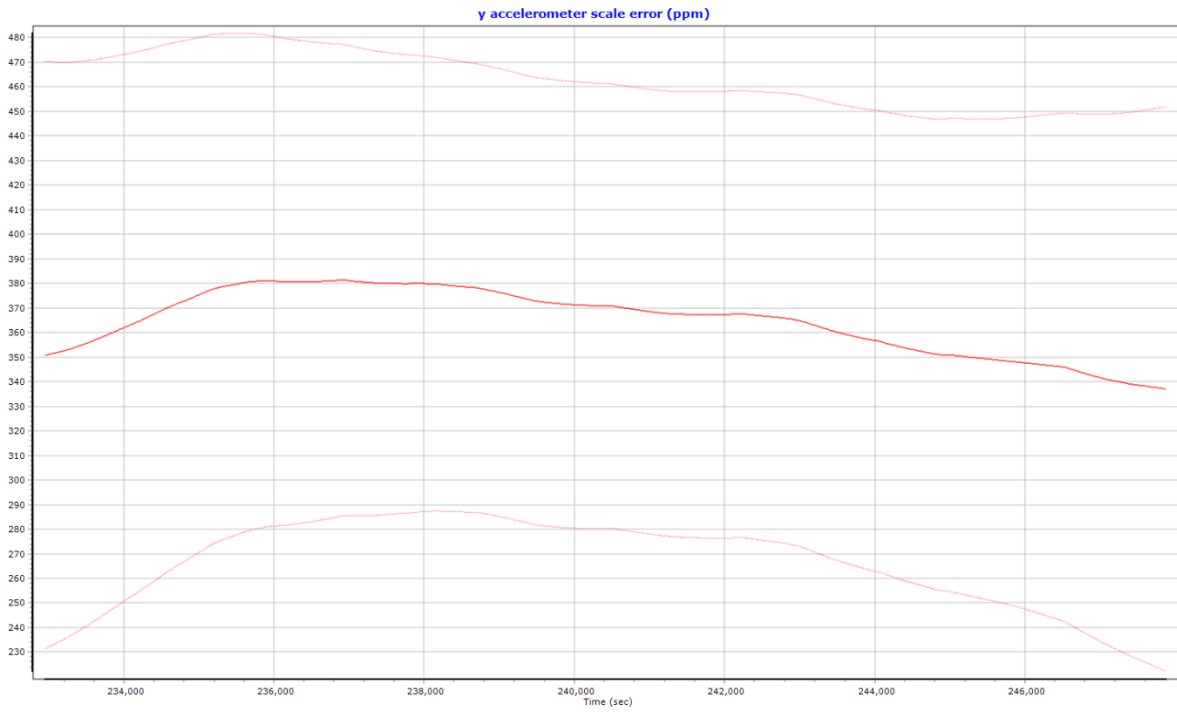
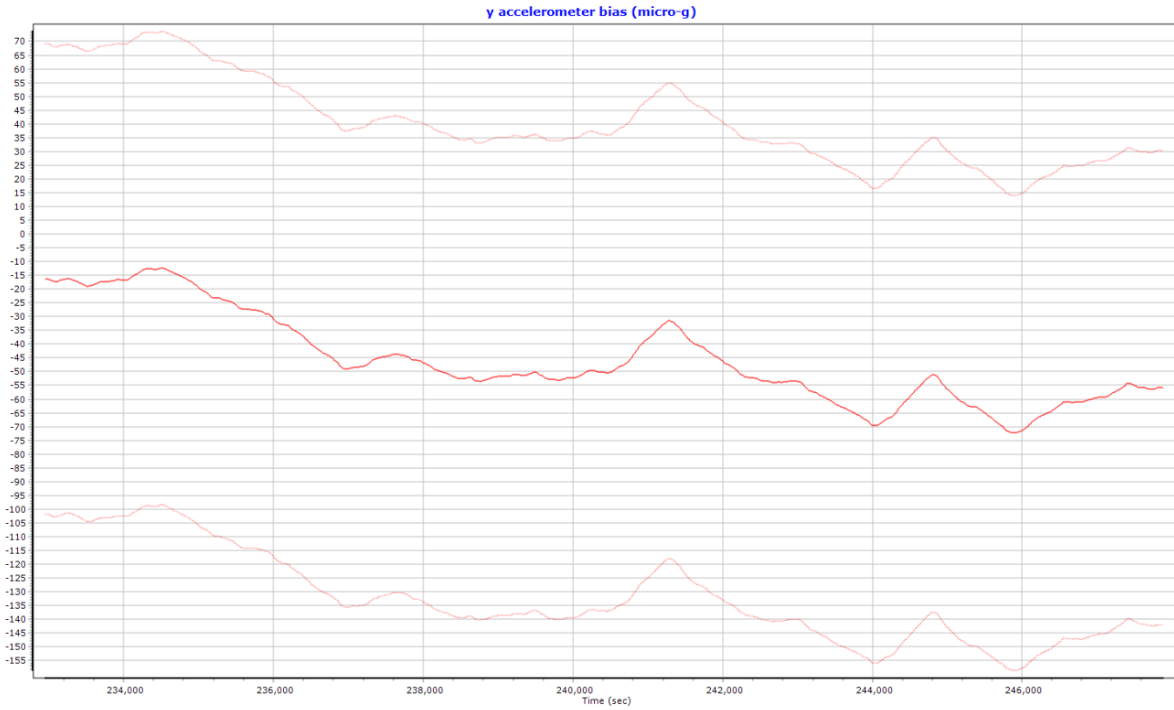
UTC Offset: 18.000

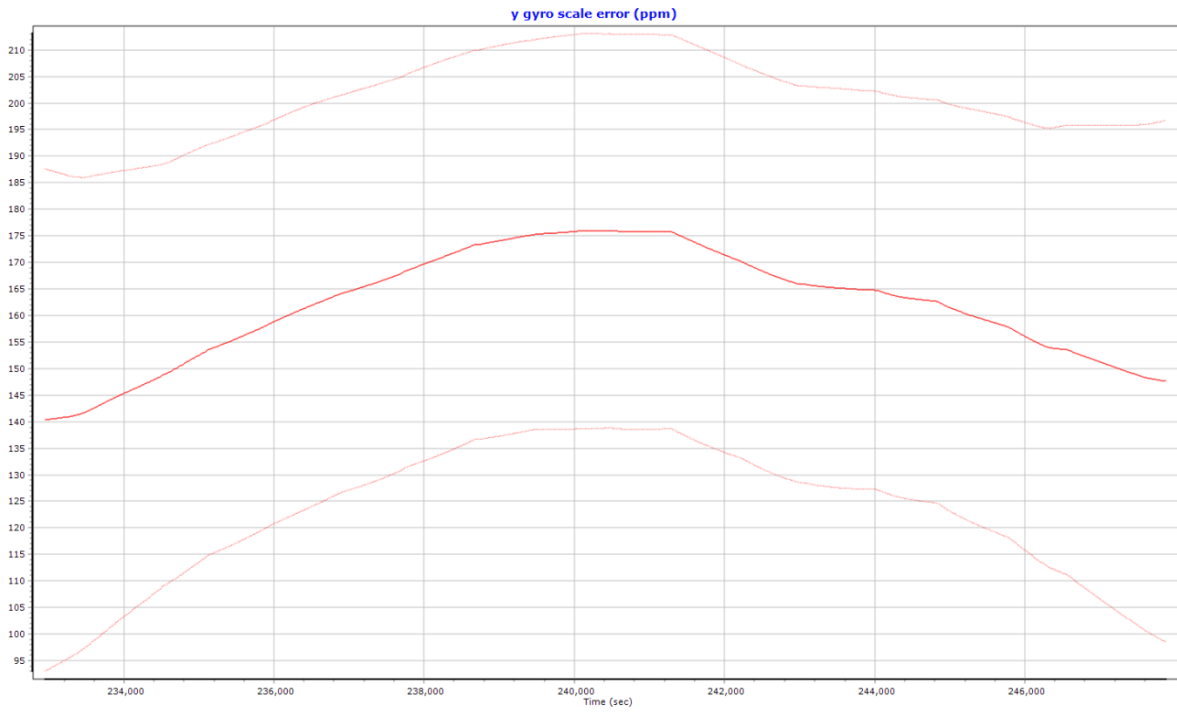
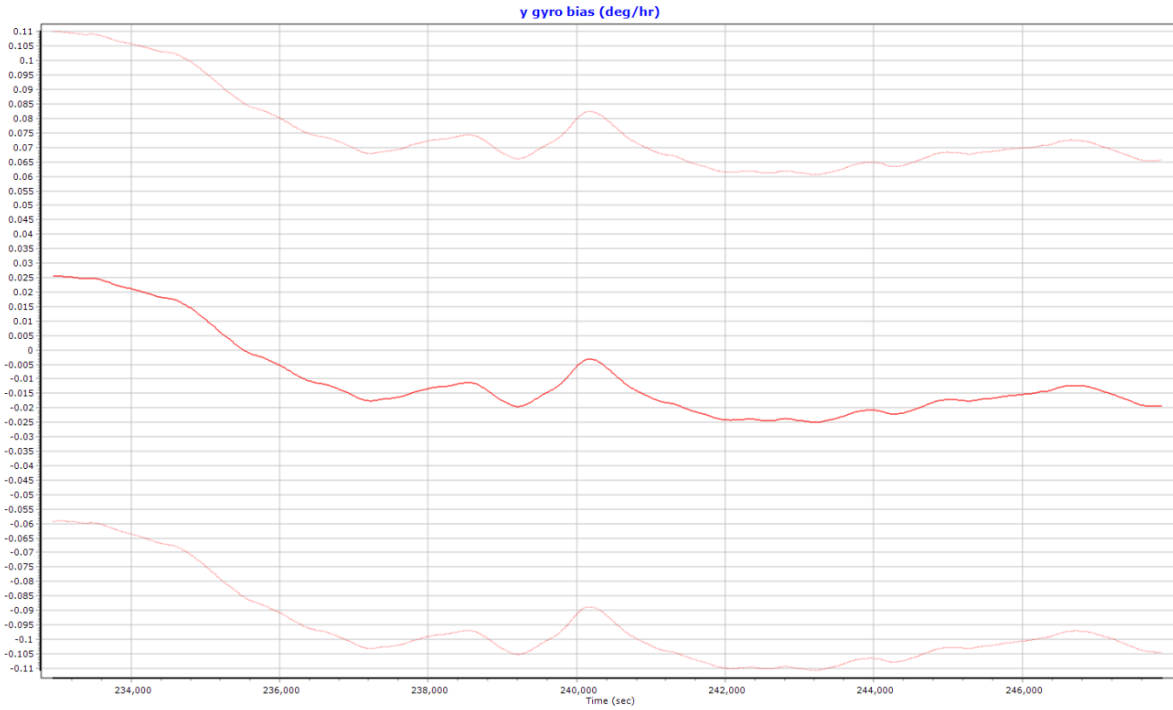
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

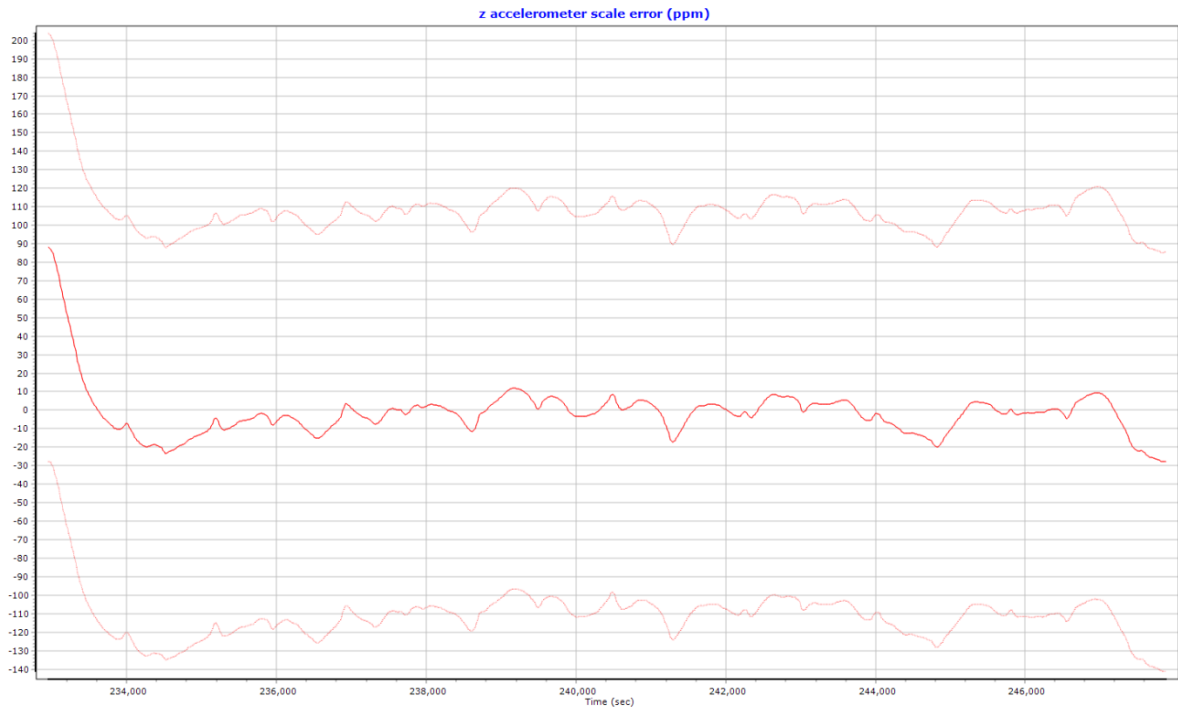
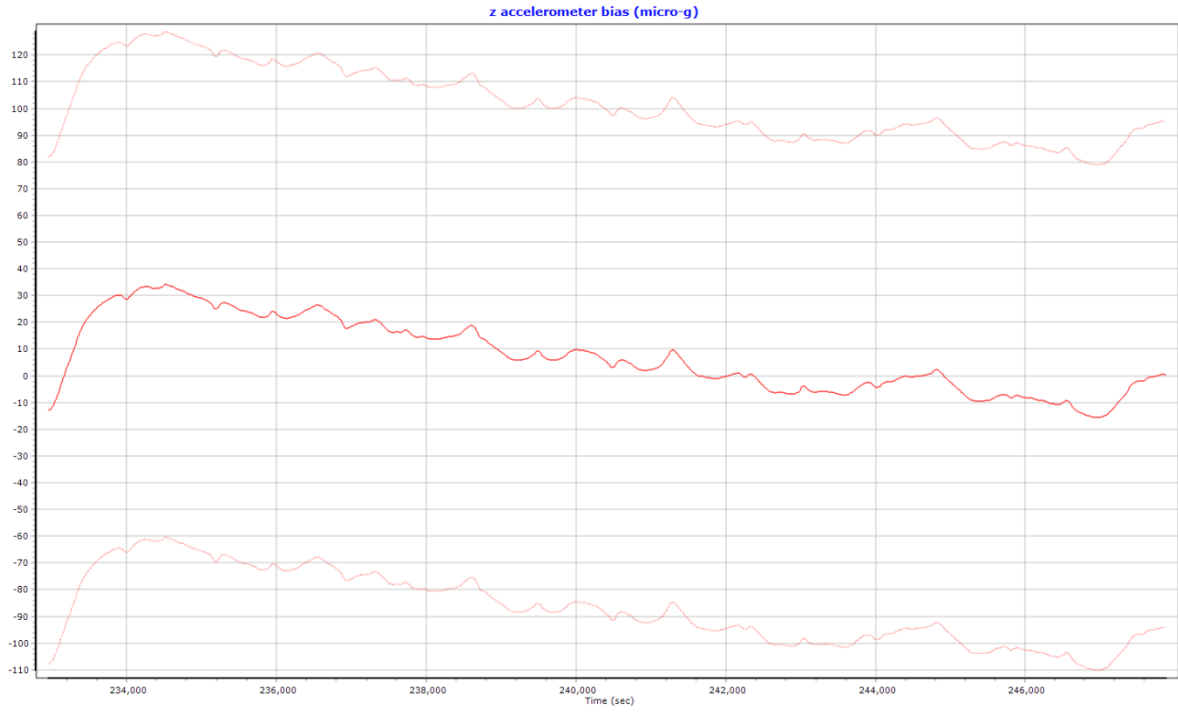
OK Cancel

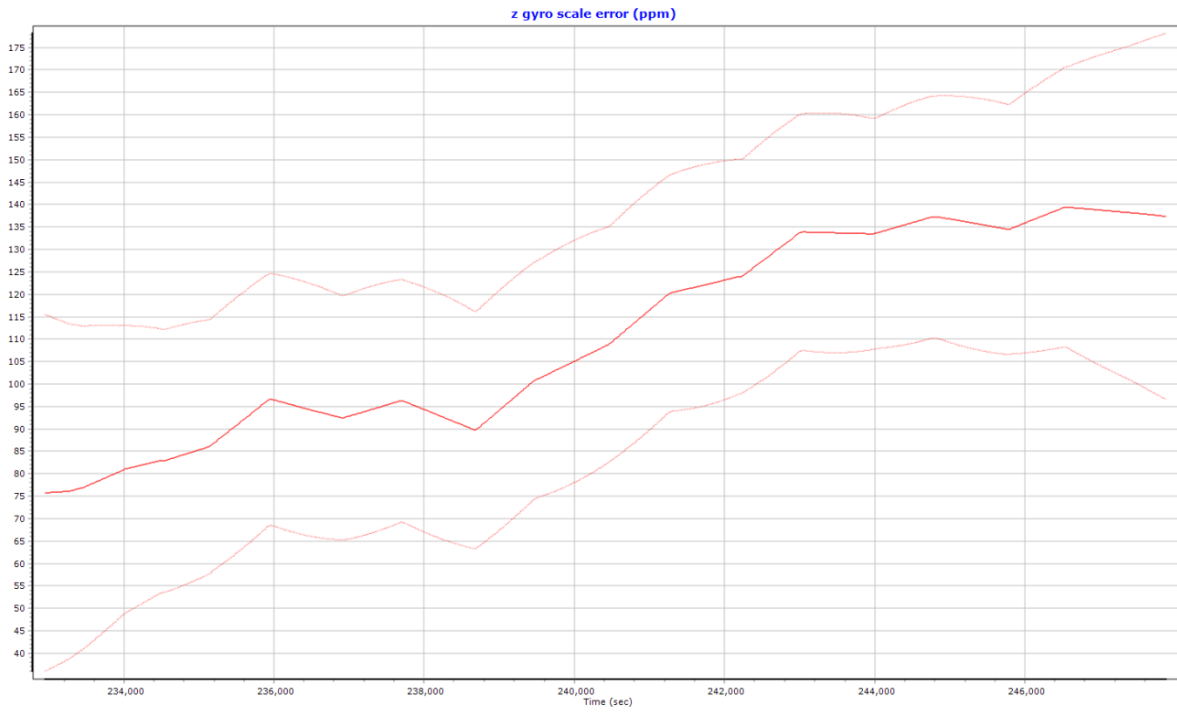
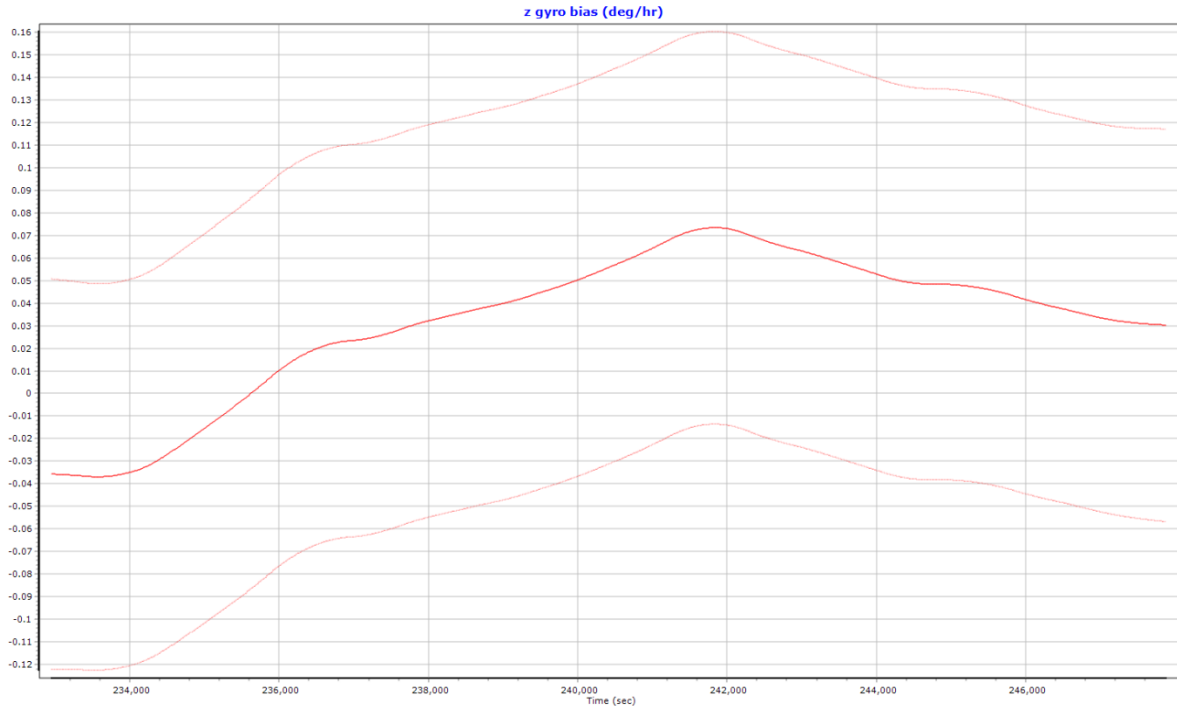




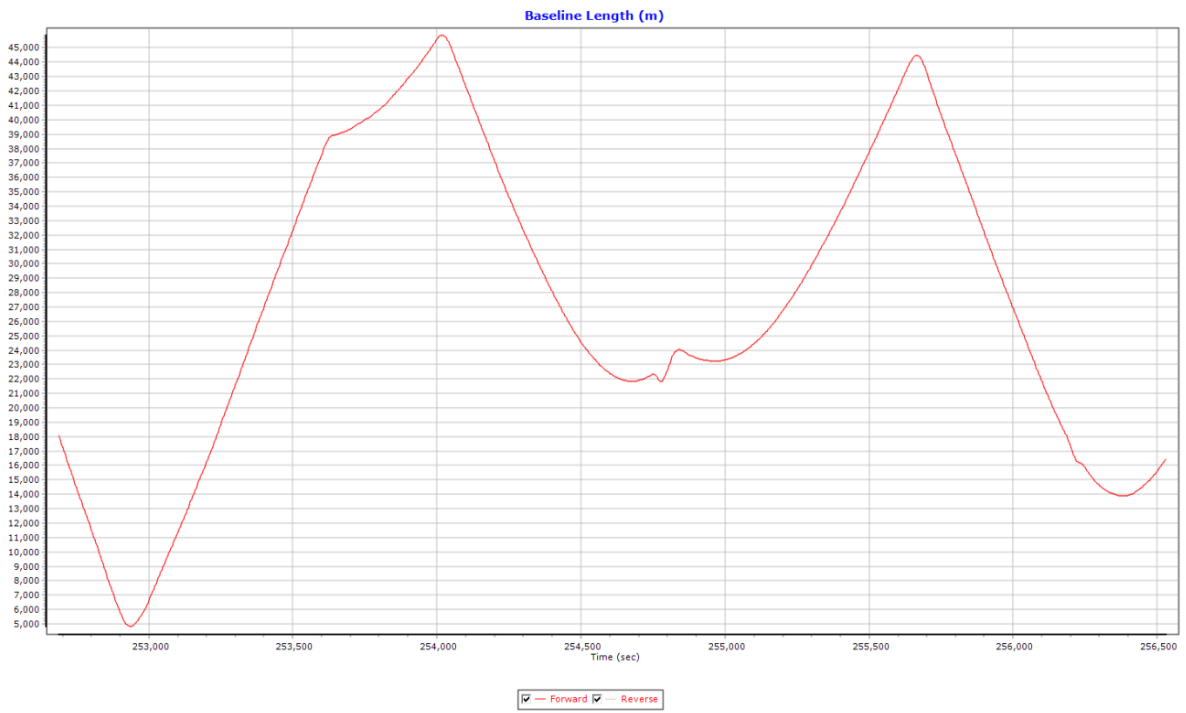




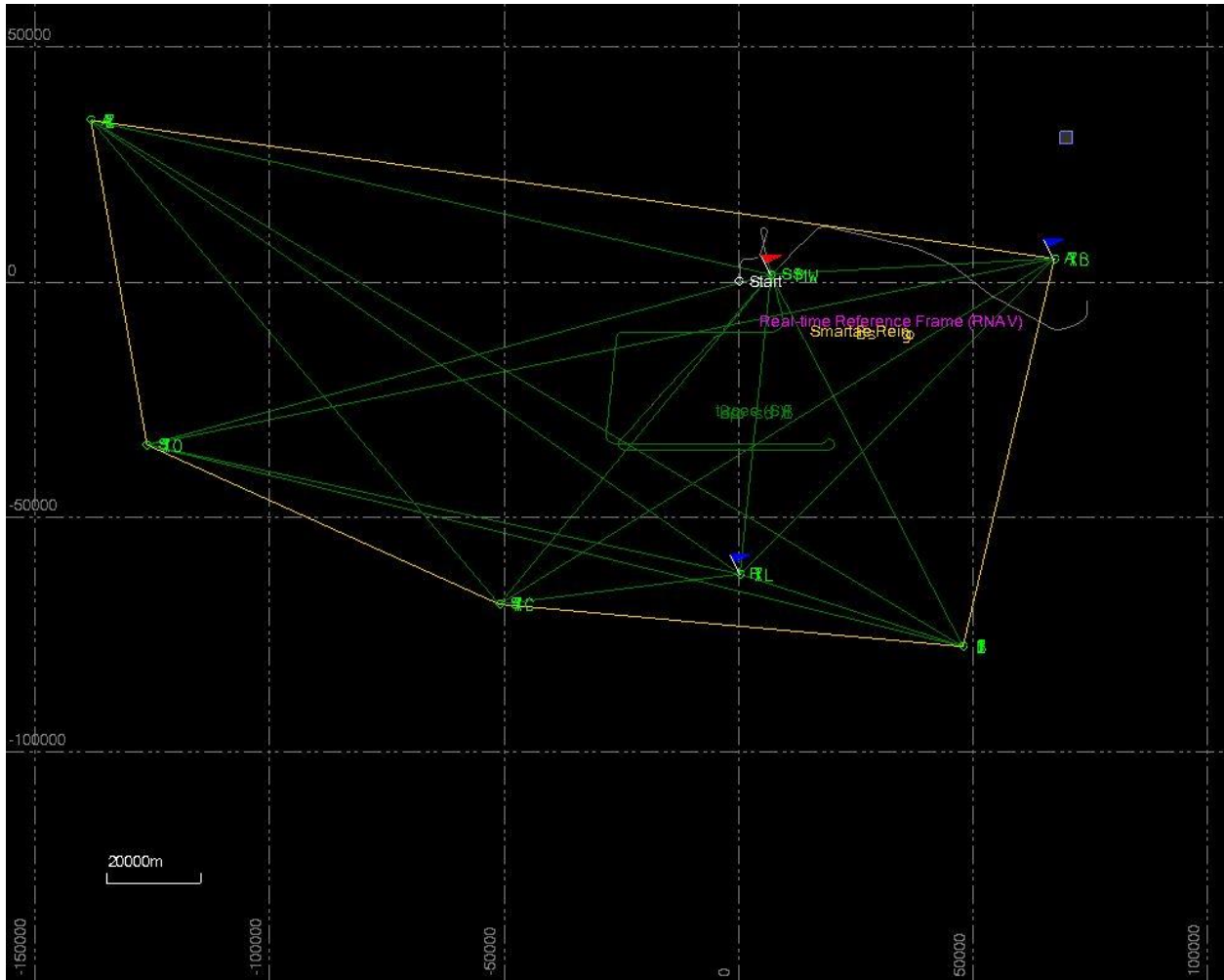




RBV18079B



Forward Reverse





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:

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

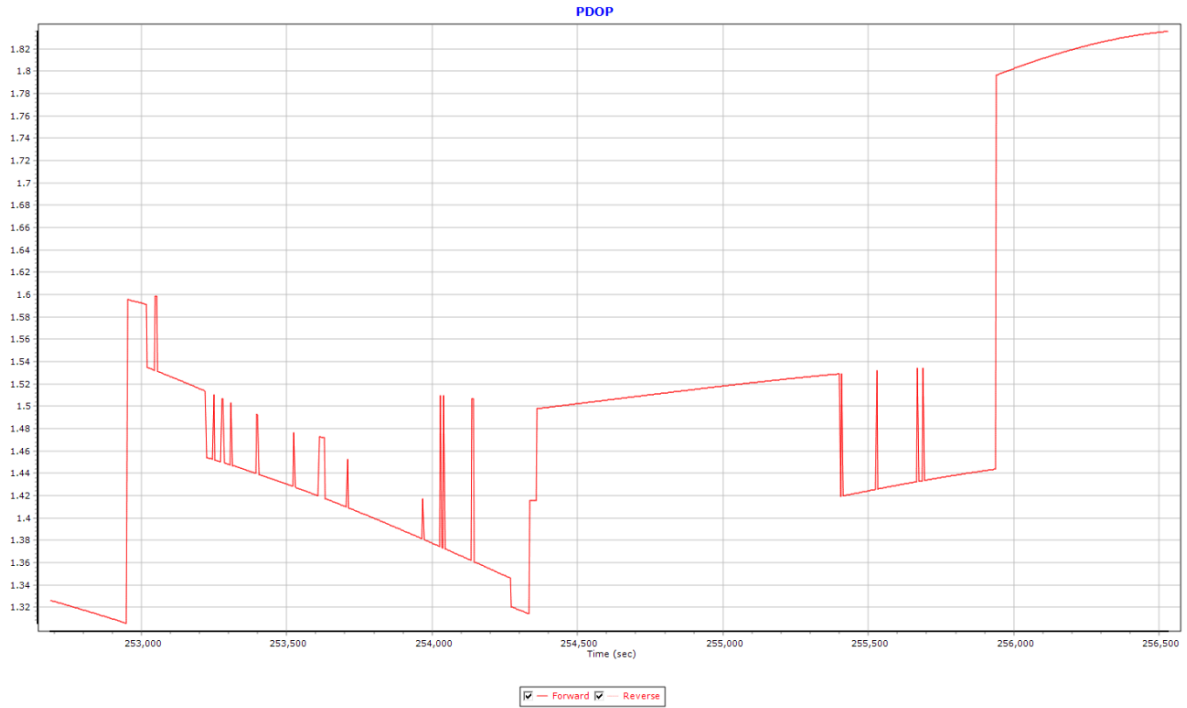
Aircraft to Stabilized Mount Mounting Angles

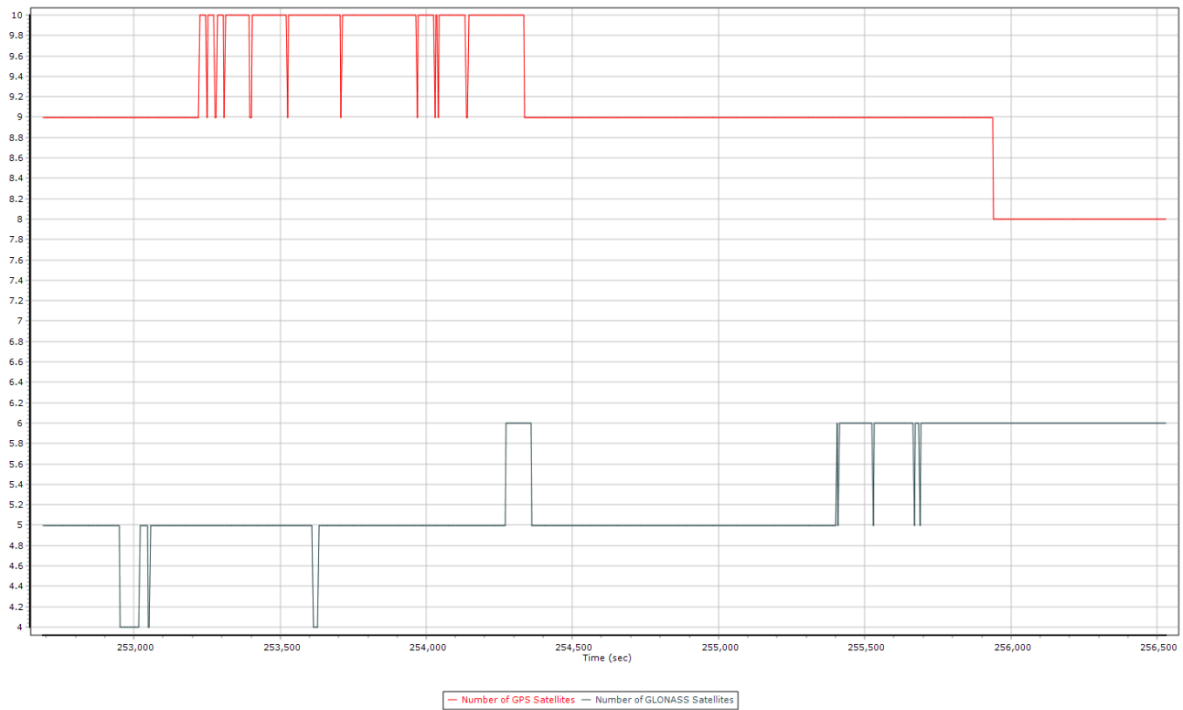
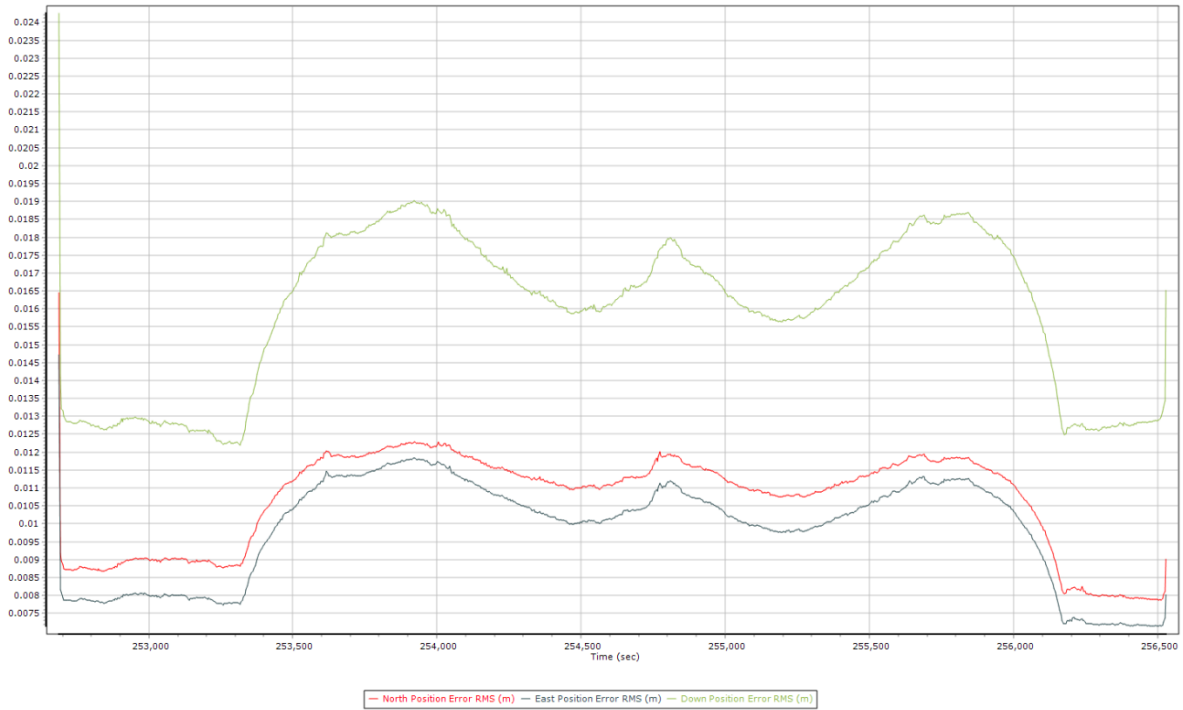
X:

Y:

Z:

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





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

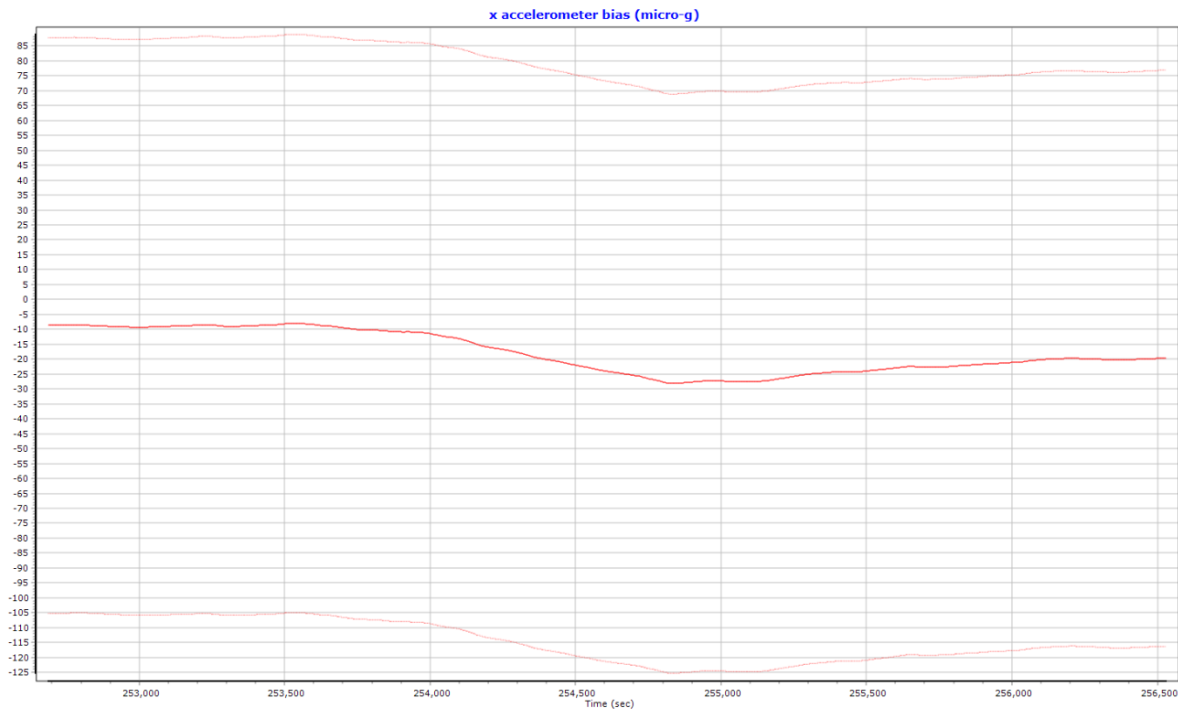
Start: 252686.154
End: 256532.047

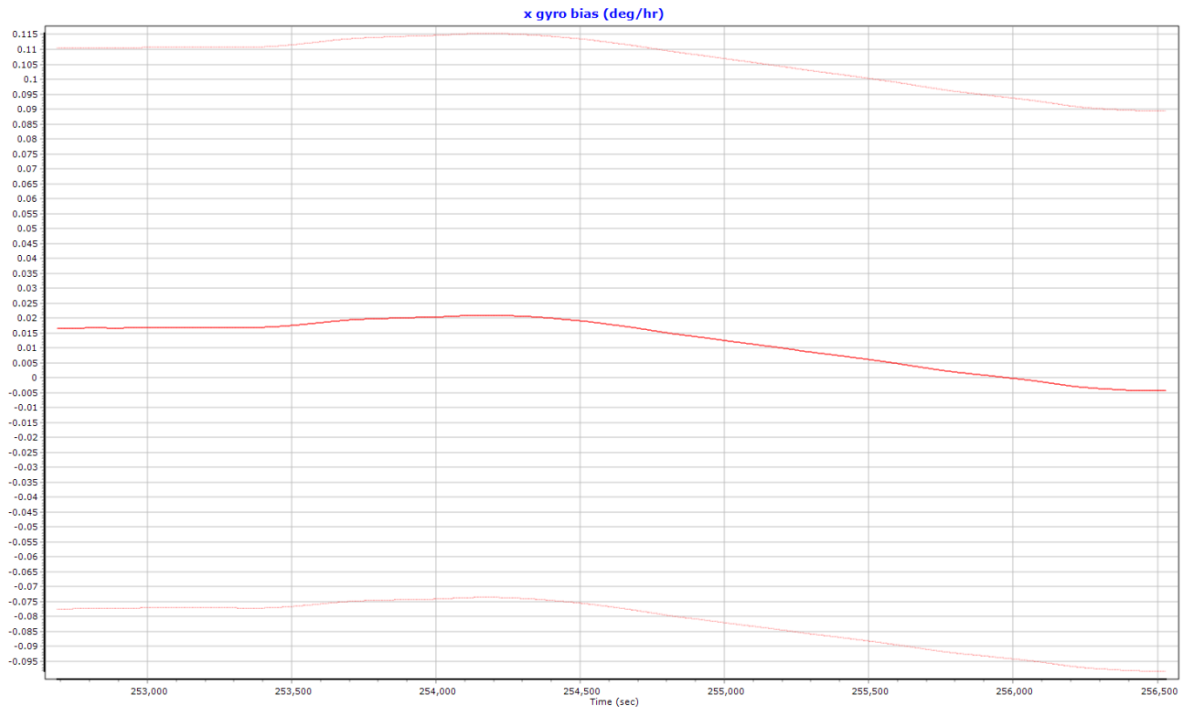
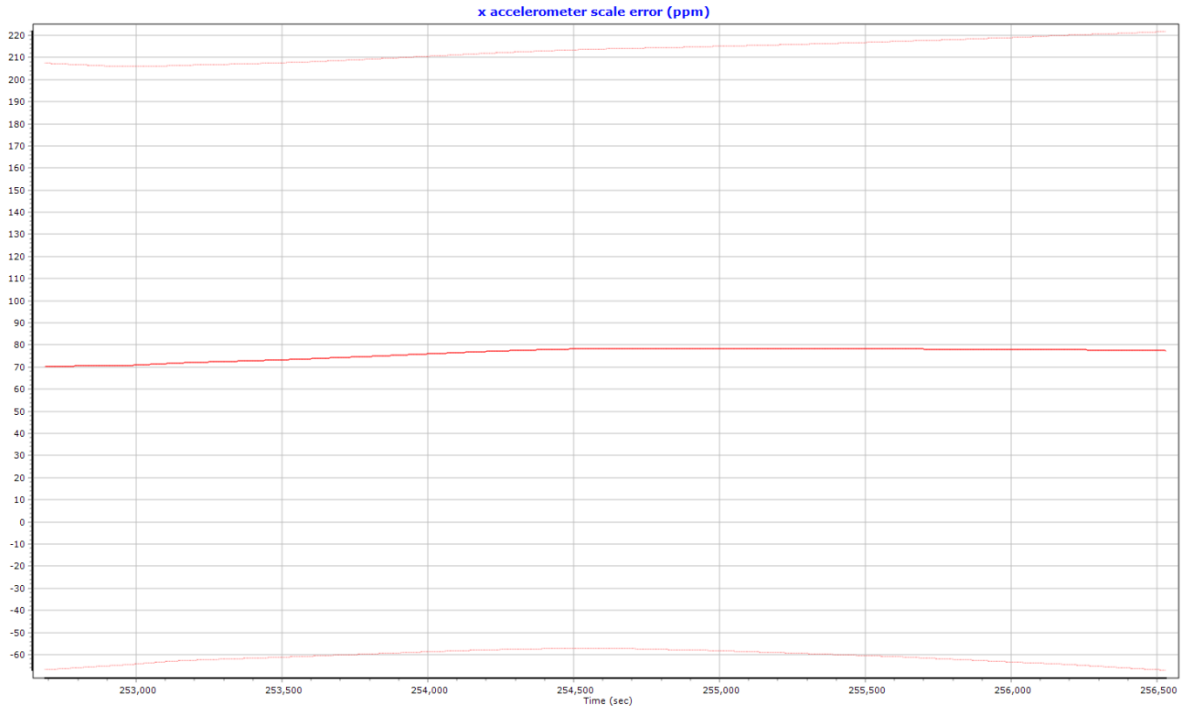
Entire time interval
 Seconds of start week

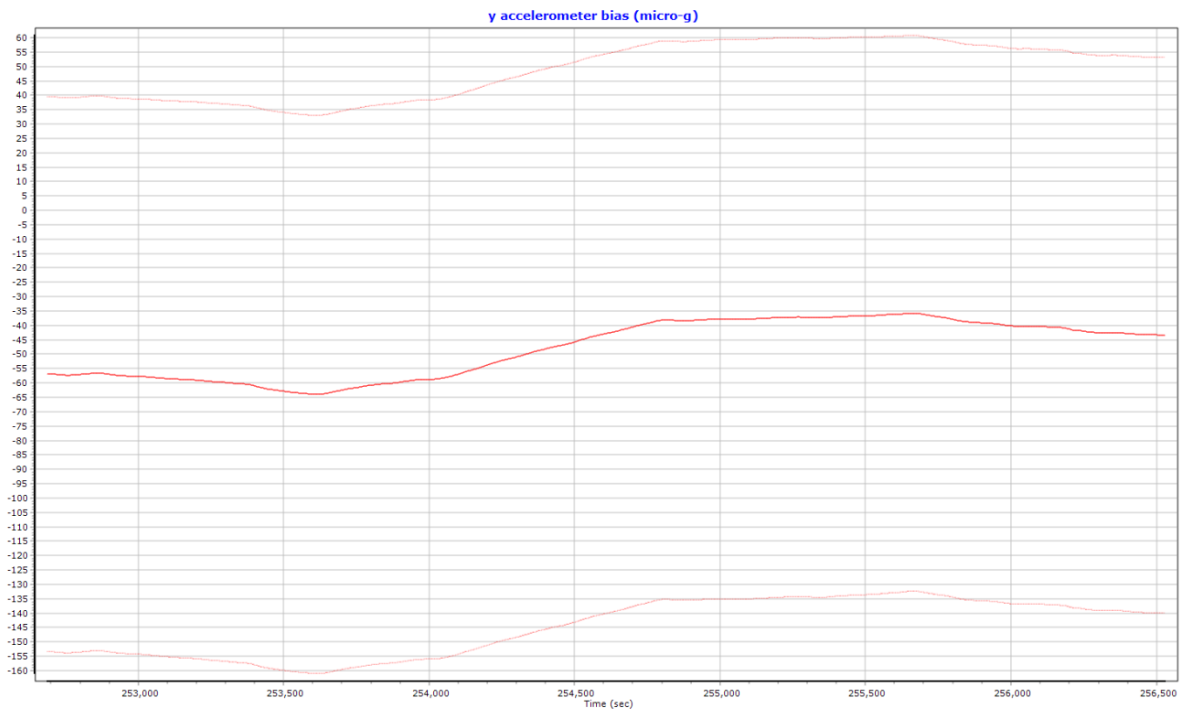
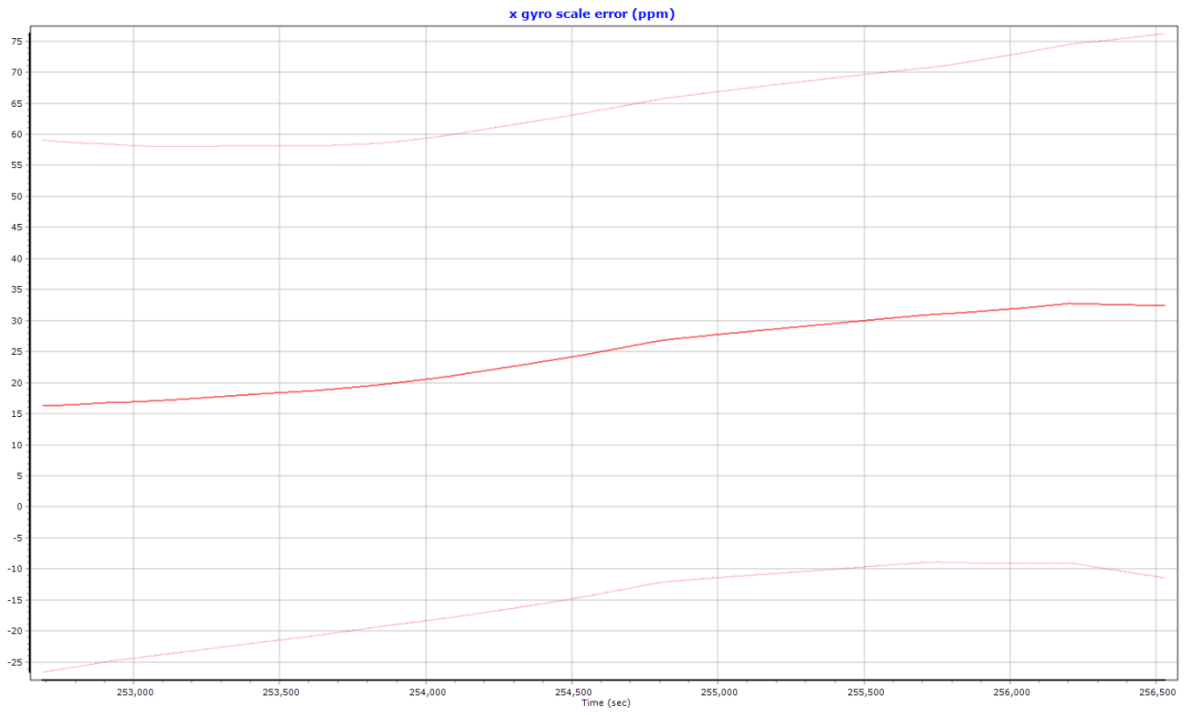
UTC Offset: 18.000

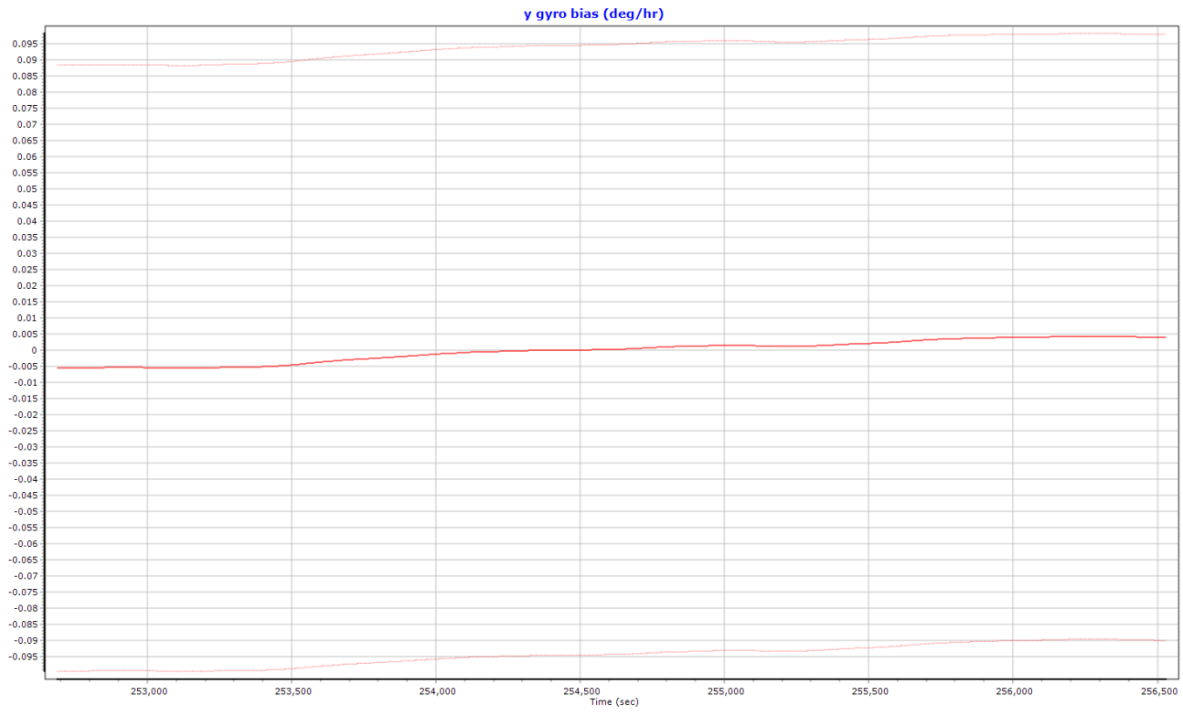
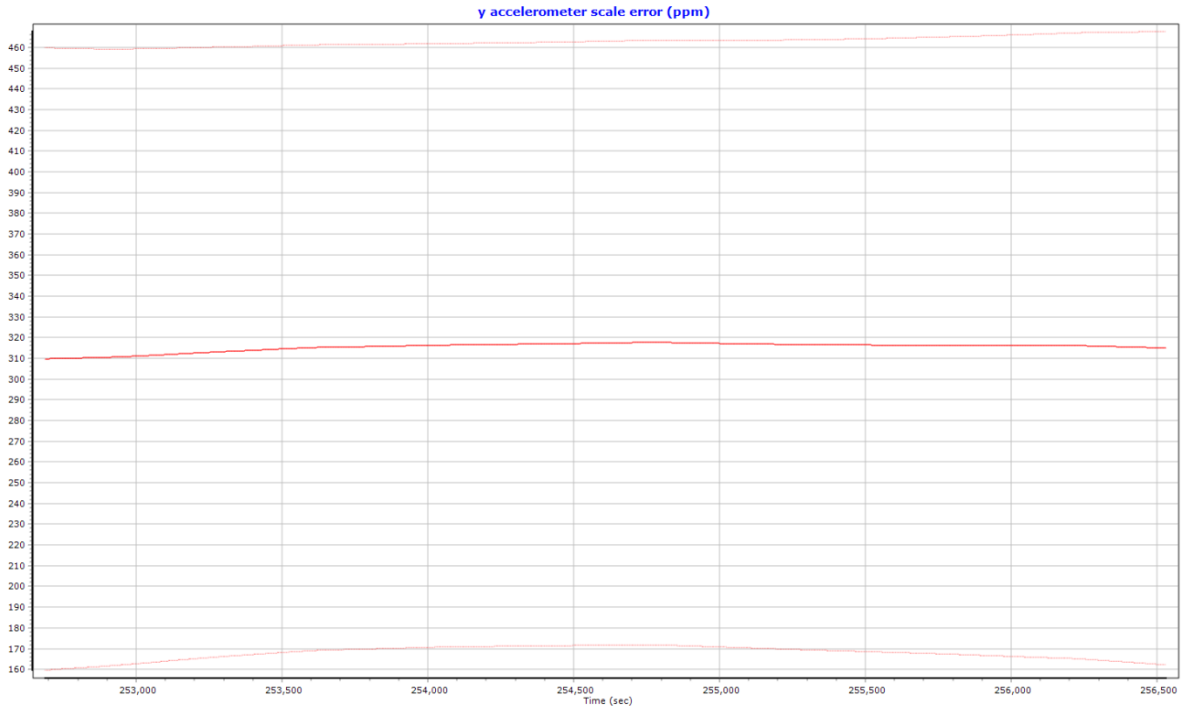
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

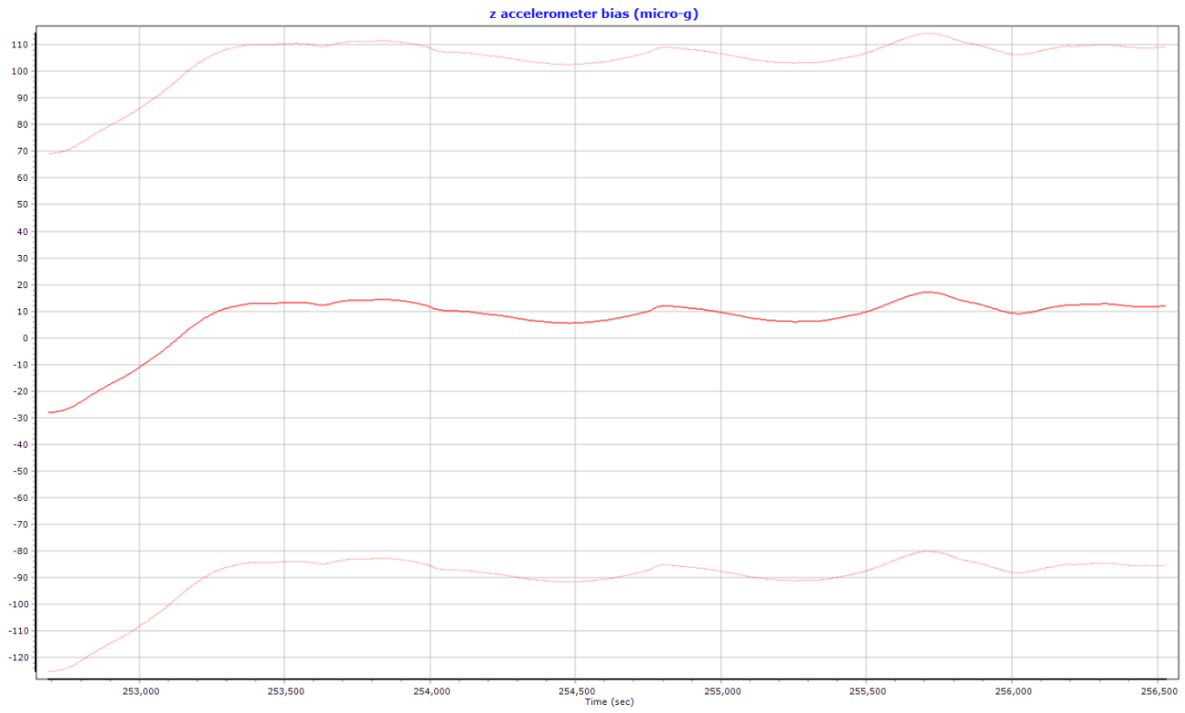
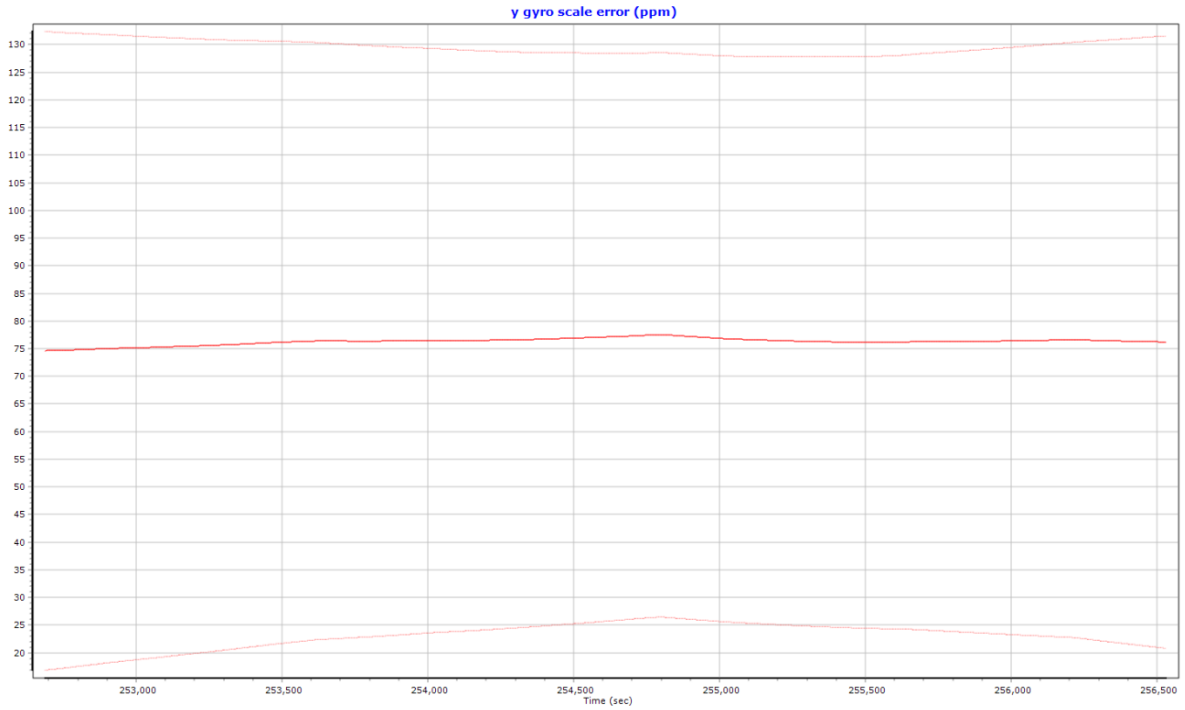
OK Cancel

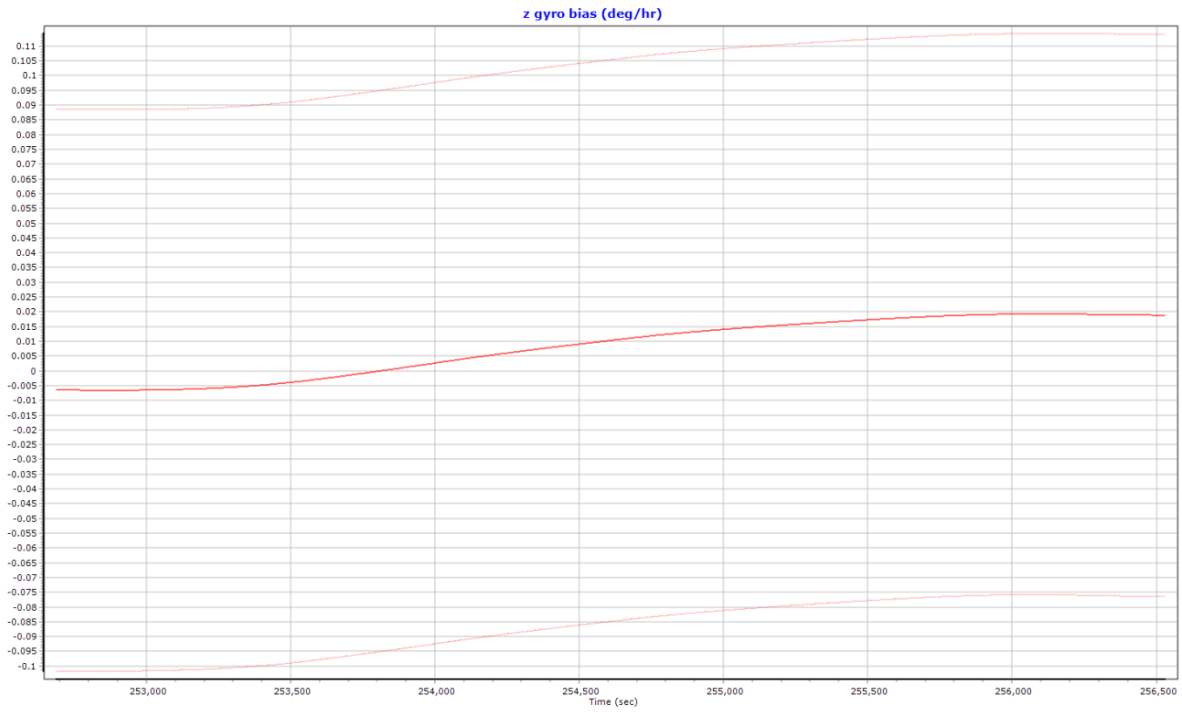
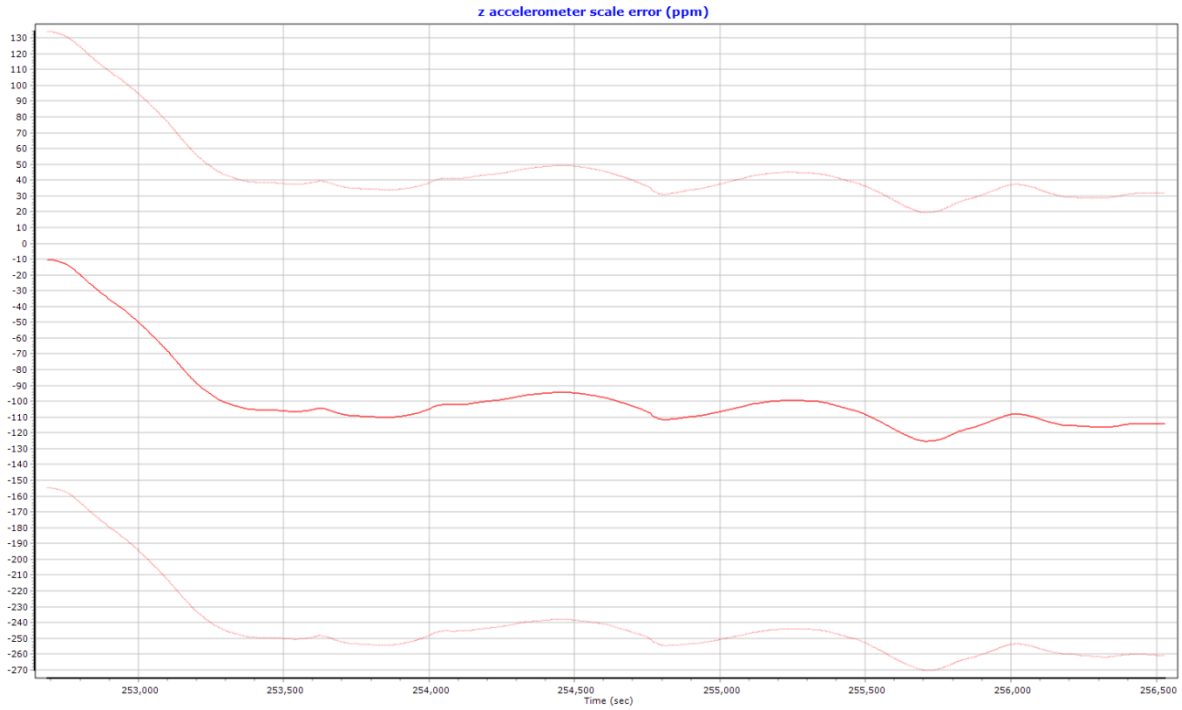


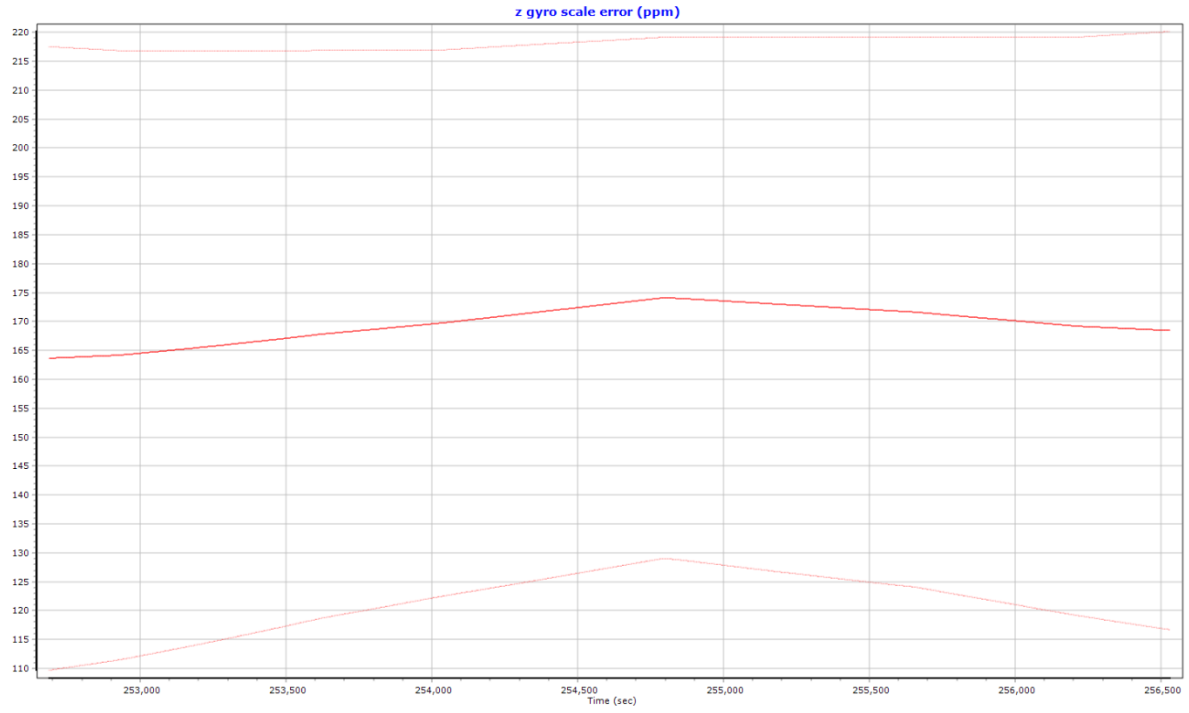




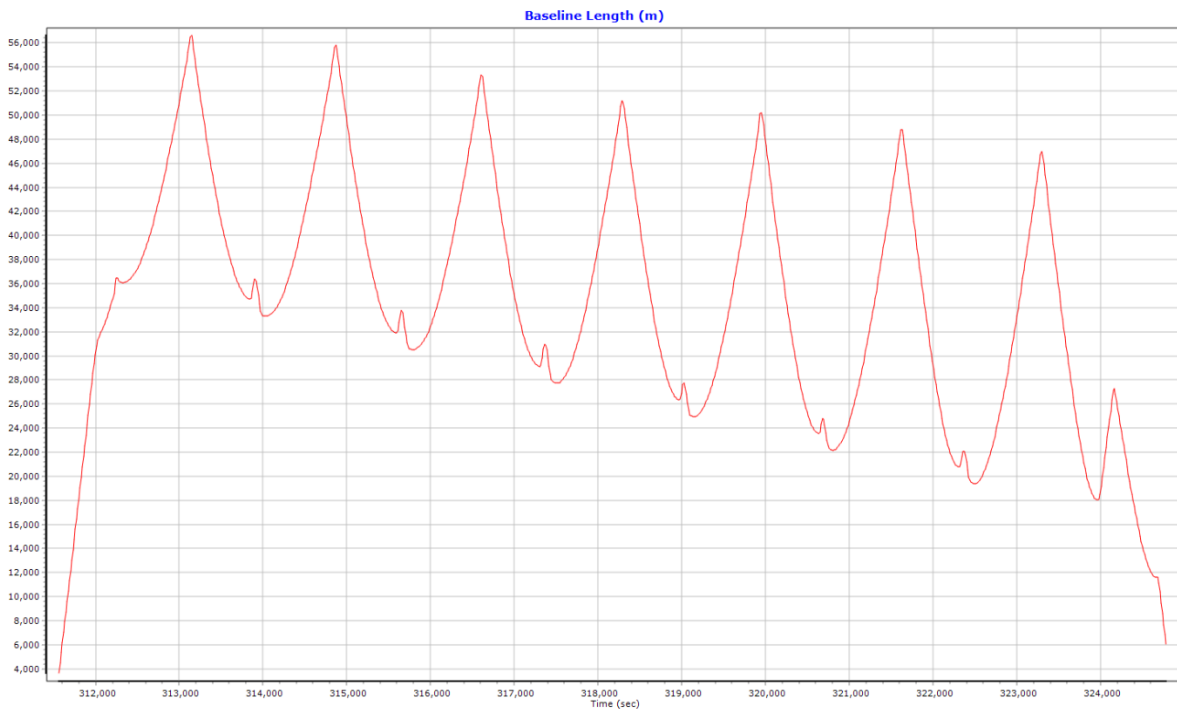
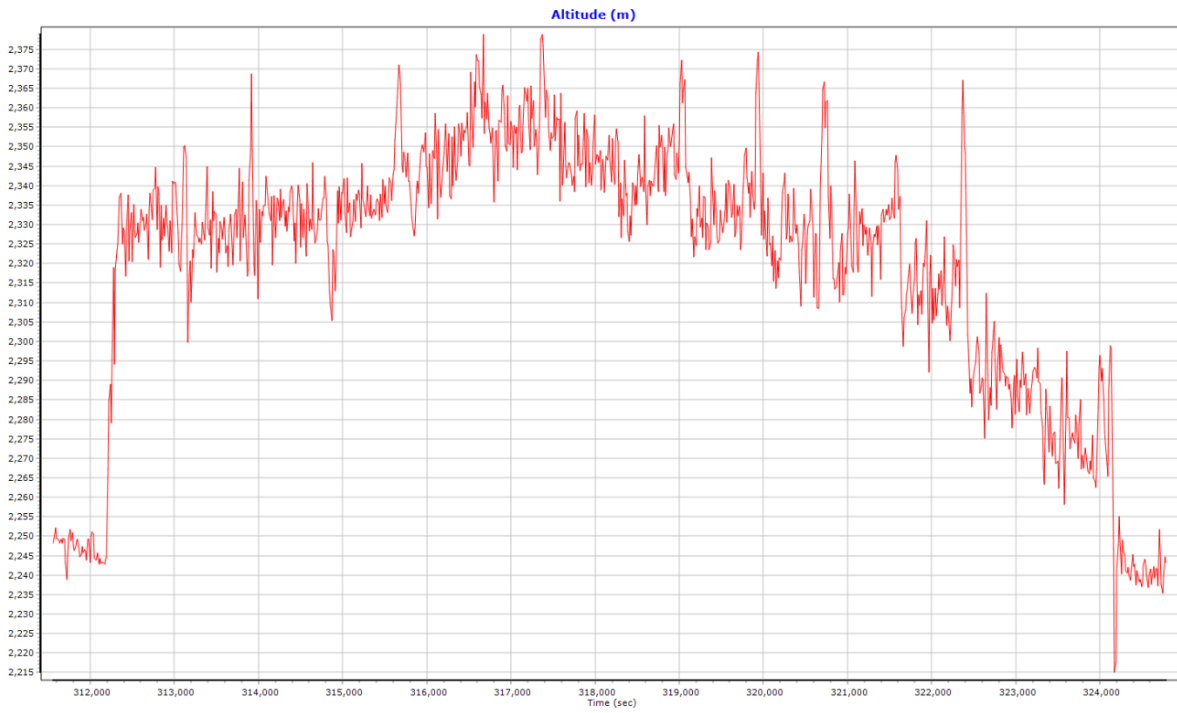


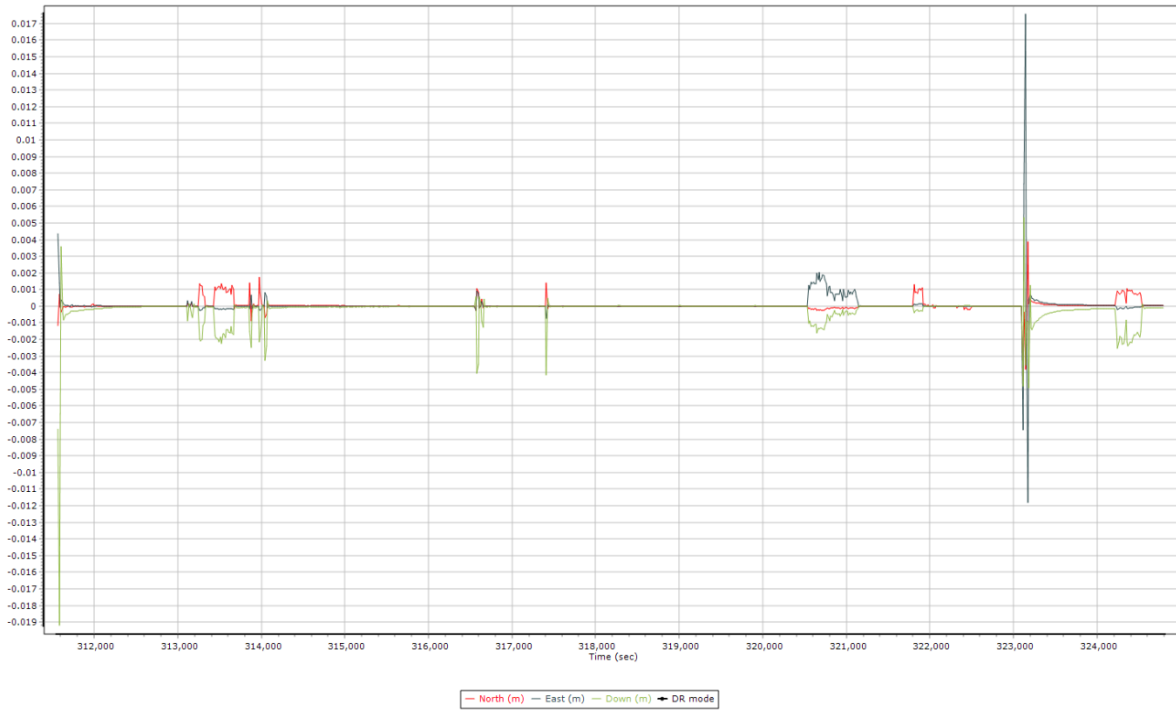
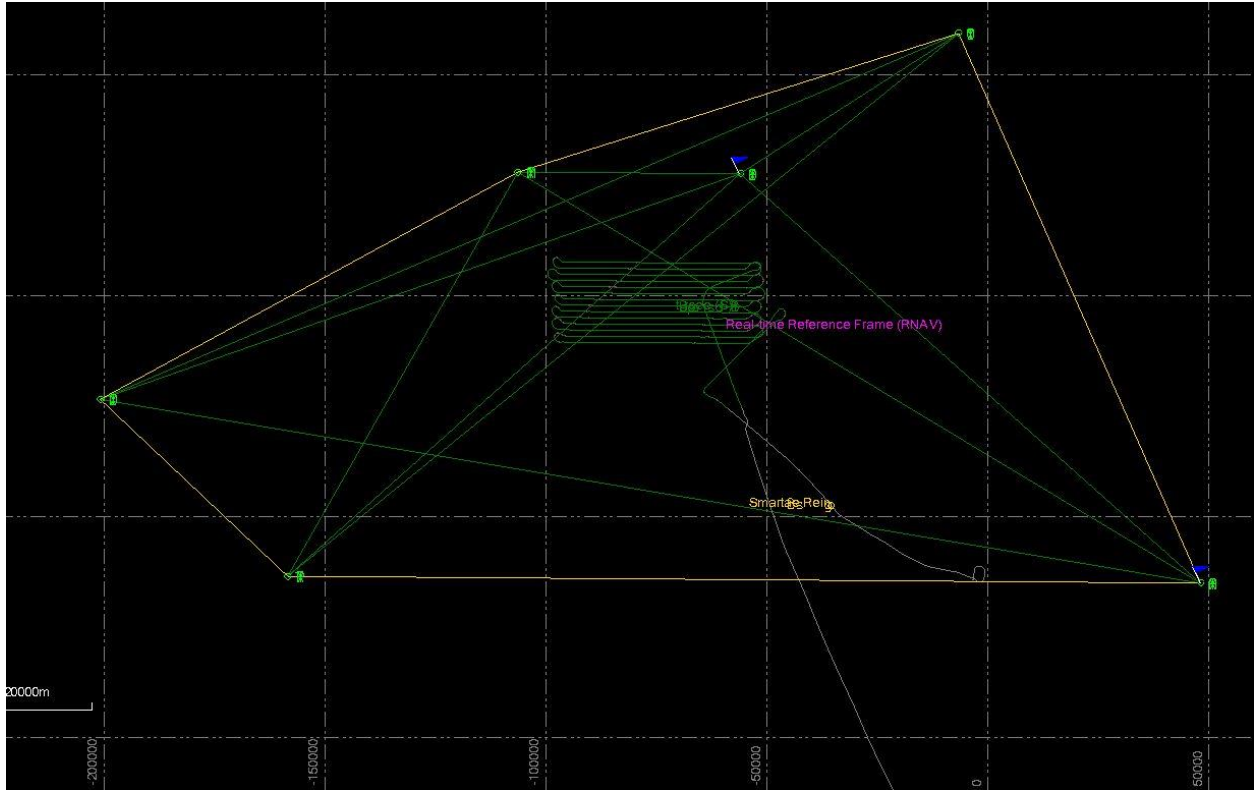






RBV18080A





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	-0.065 m
Y	0.014 m
Z	-1.021 m

Aircraft to Stabilized Mount Mounting Angles

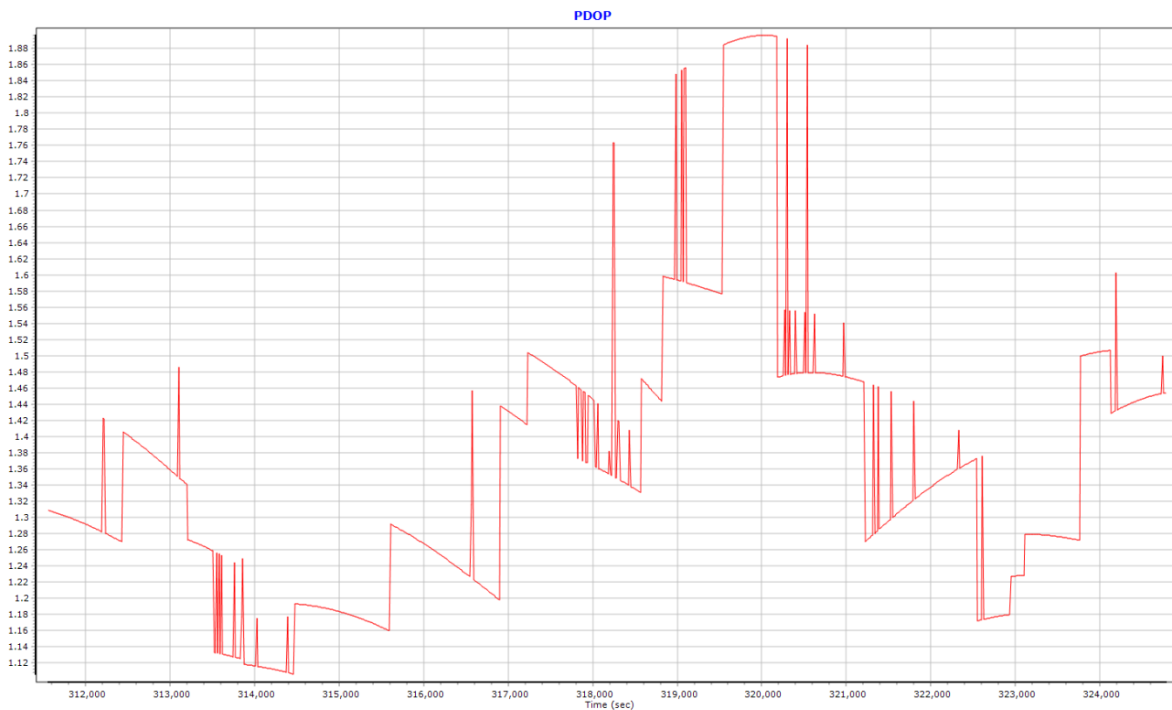
X	0.000 deg
Y	0.000 deg
Z	0.000 deg

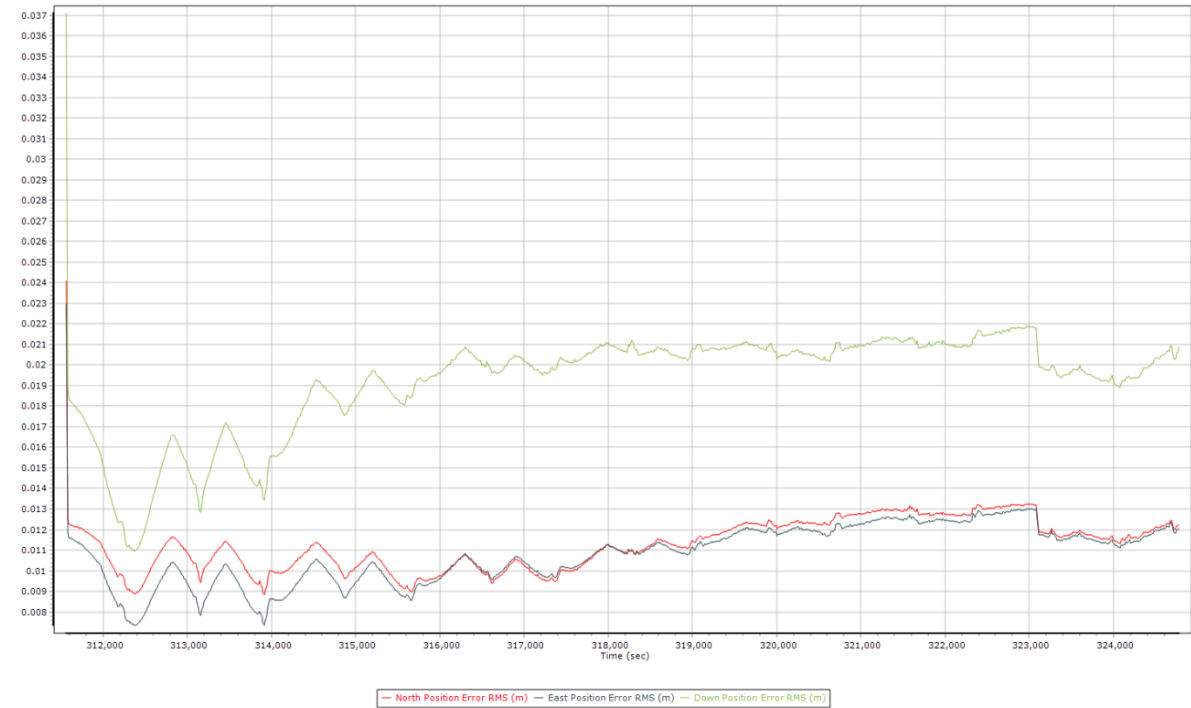
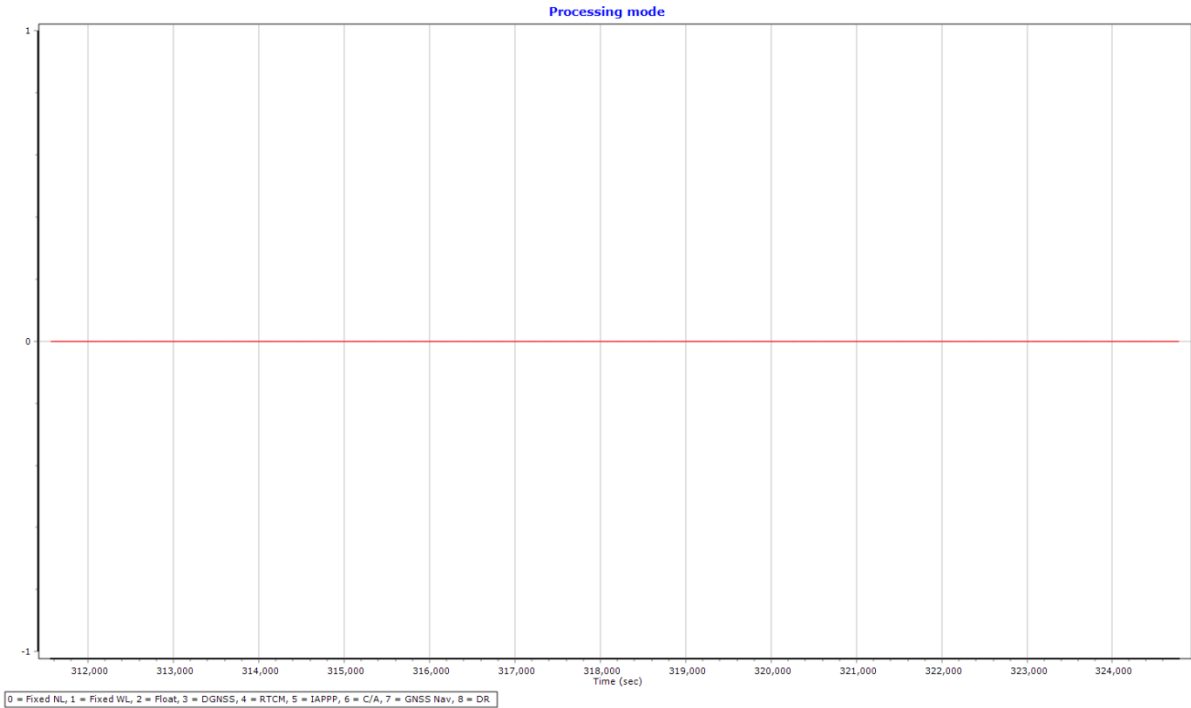
Standard Deviation

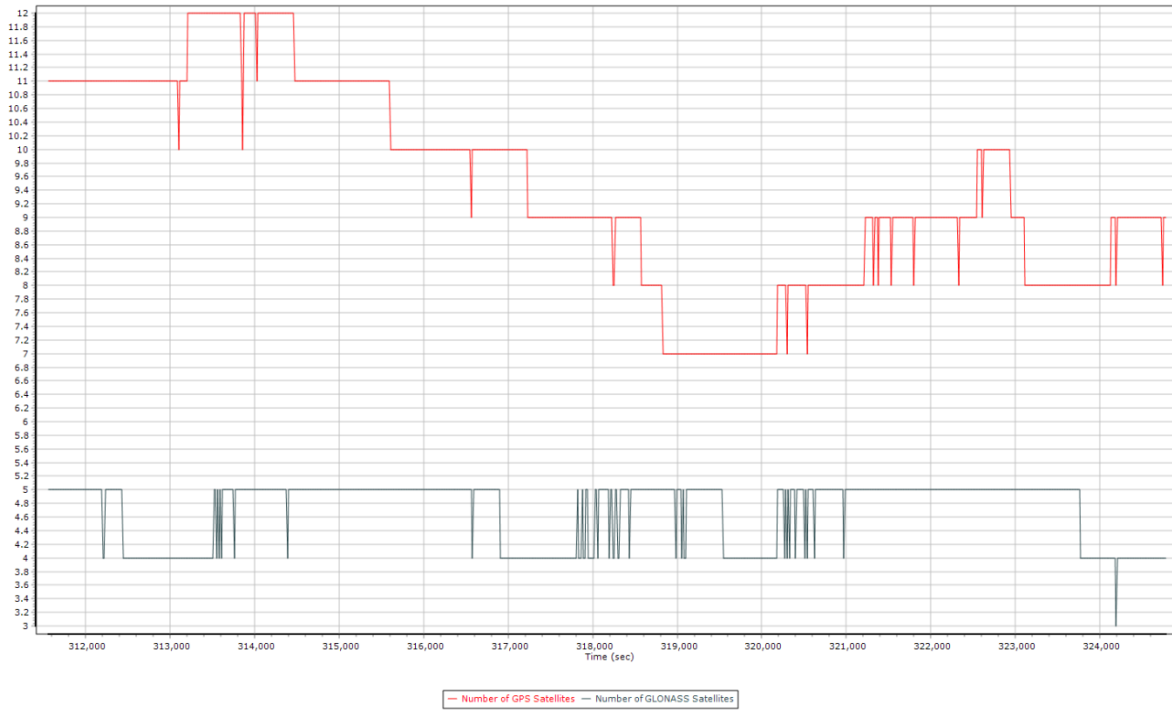
<3cm 10cm 50cm 1m 10m

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

OK Cancel







Project Settings [X]

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

Timing

Start: 311619.840 Data: [] Incr. (sec): [] ▲

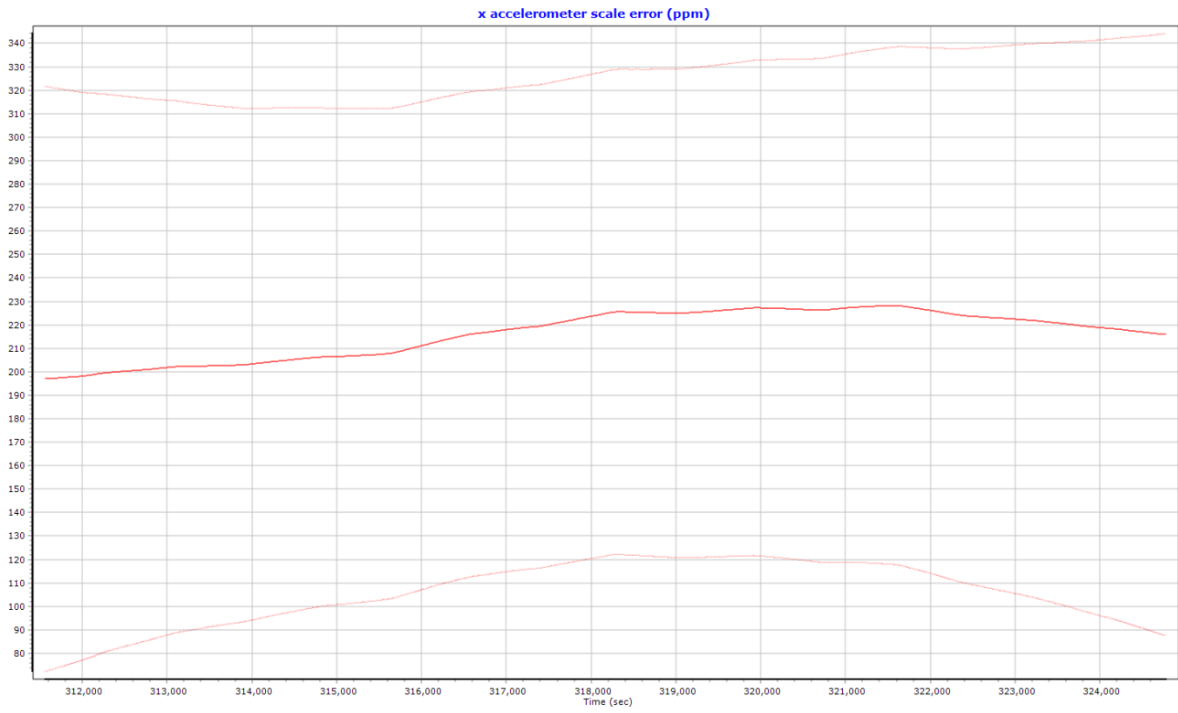
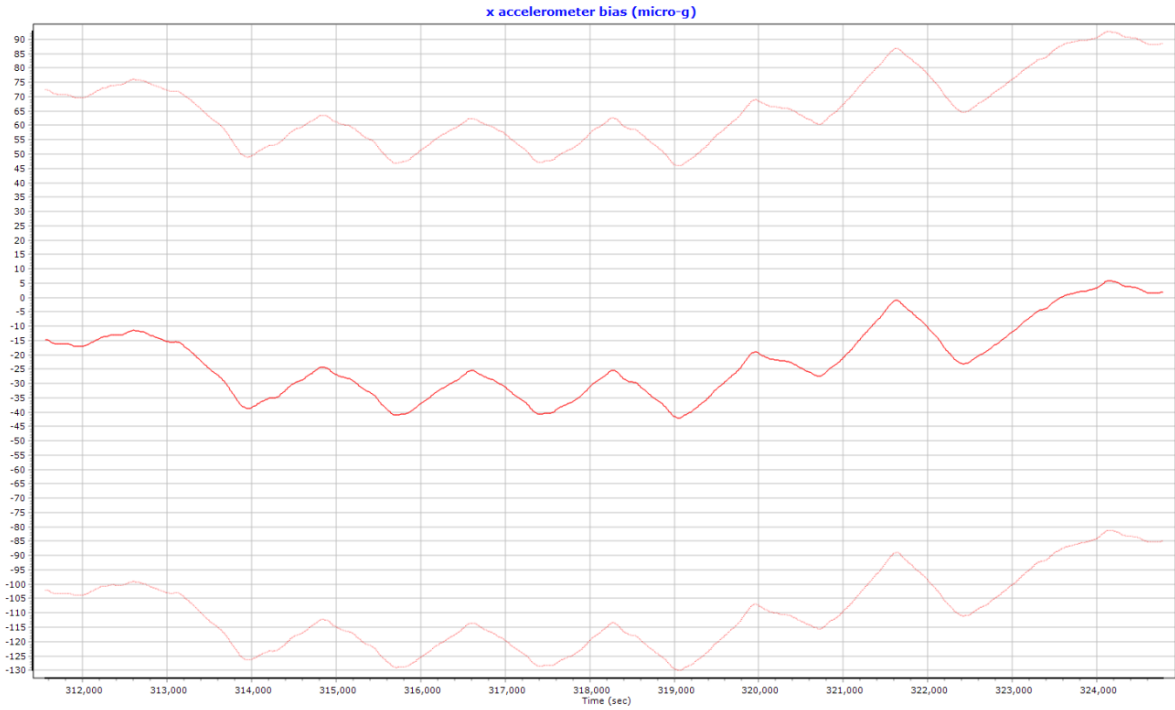
End: 324802.884 Output Record: 0.005000

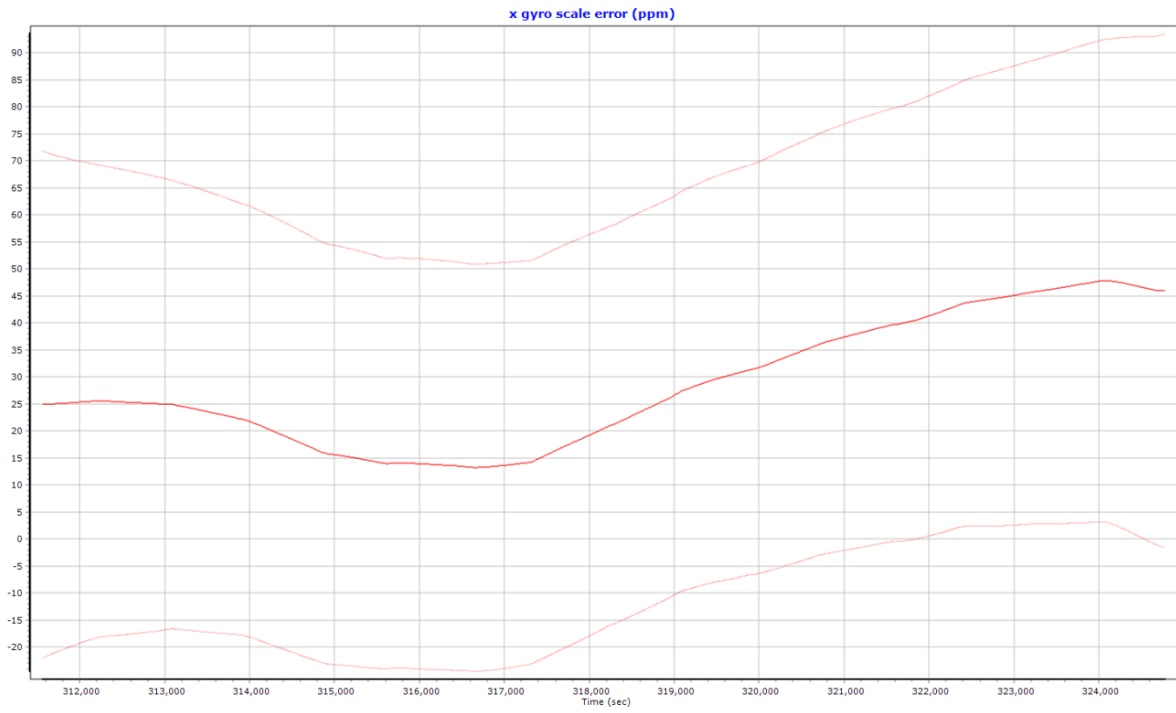
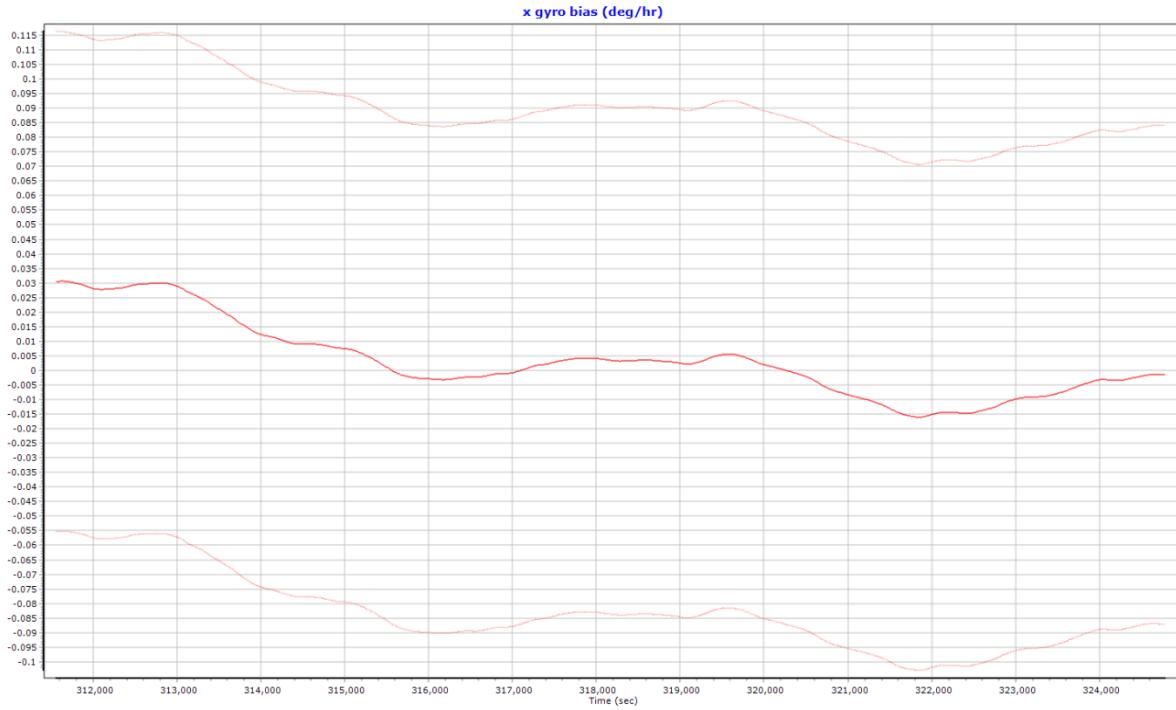
Entire time interval IMU: 0.005000

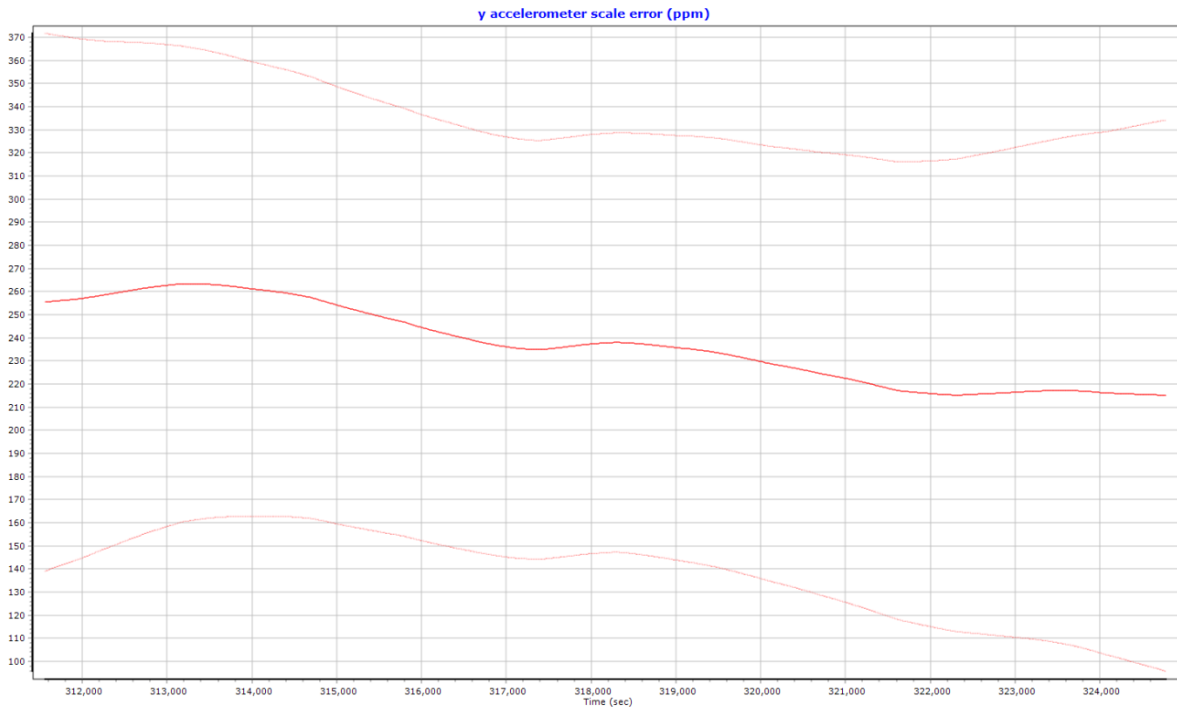
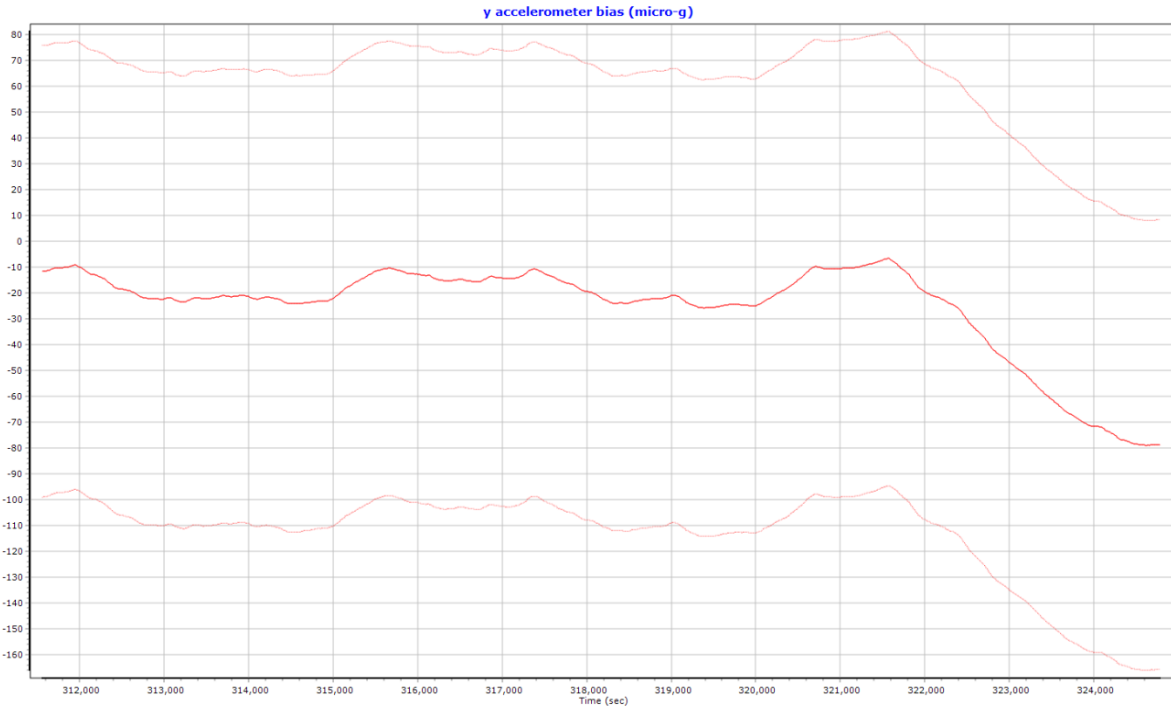
Seconds of start week Primary GNSS: 1.000000 ▼

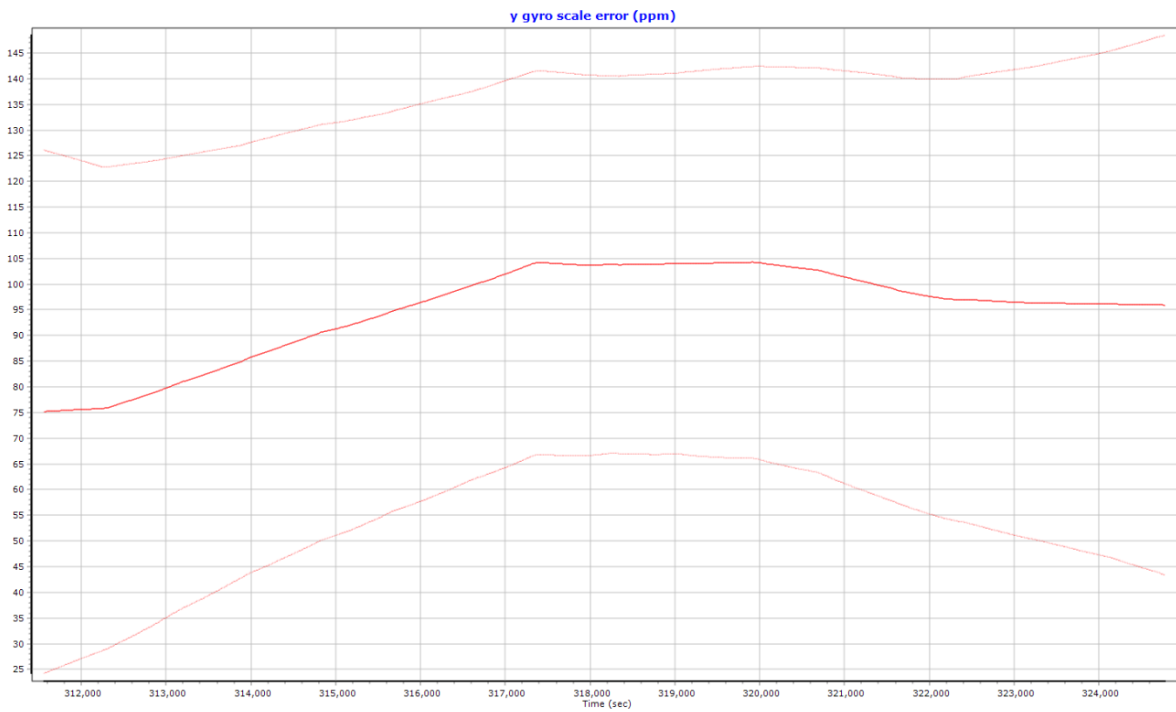
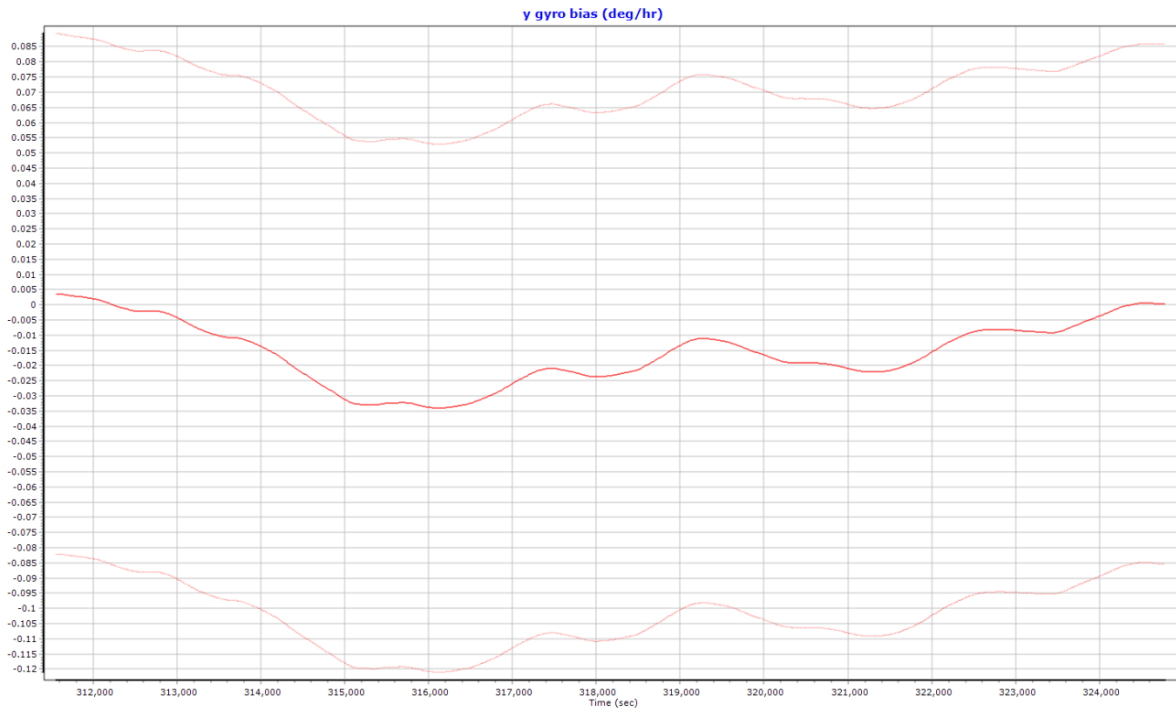
UTC Offset: 18.000

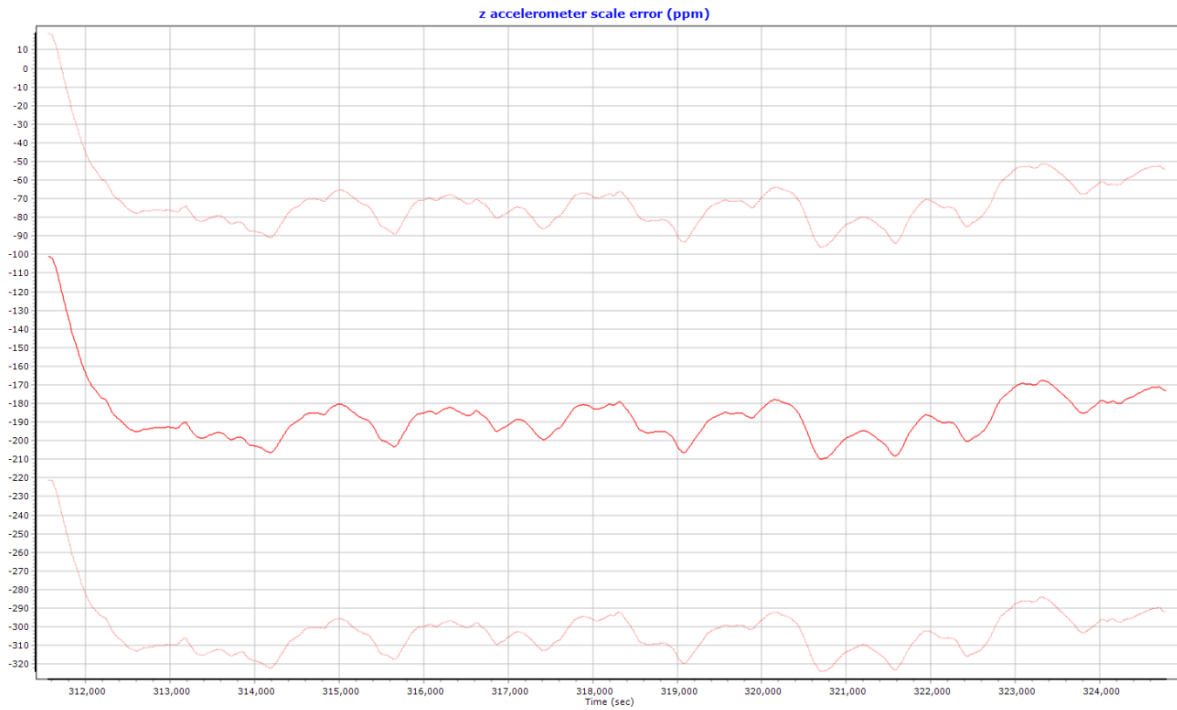
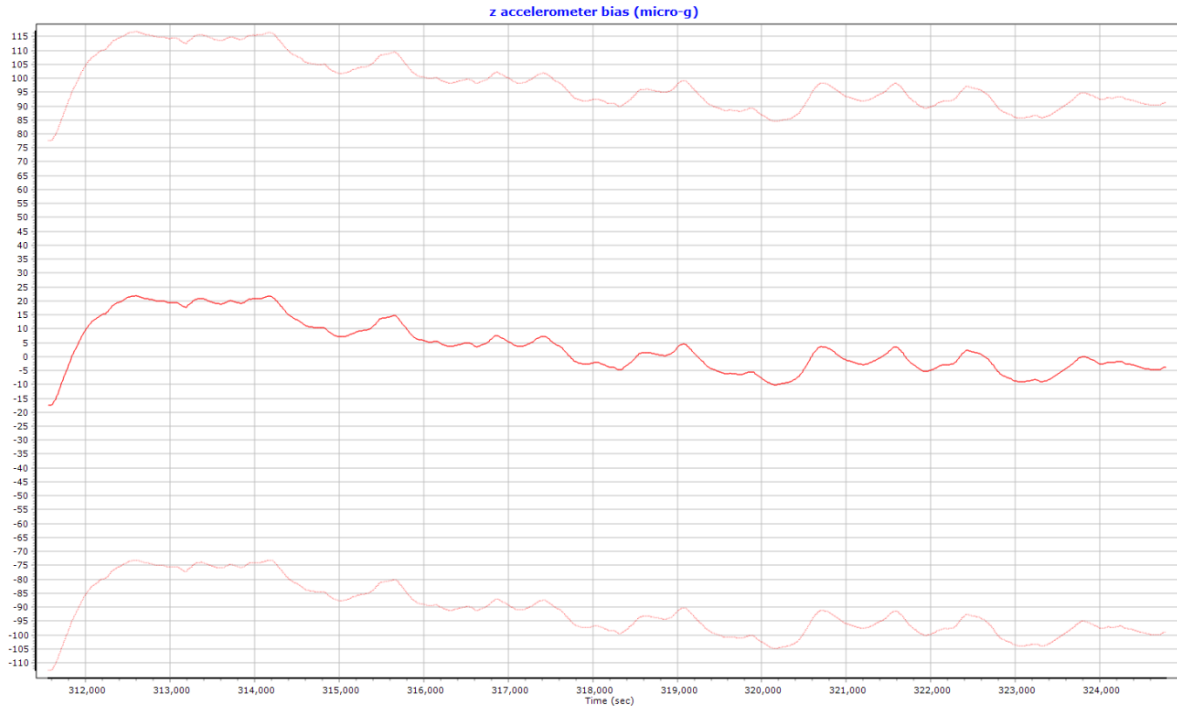
OK Cancel

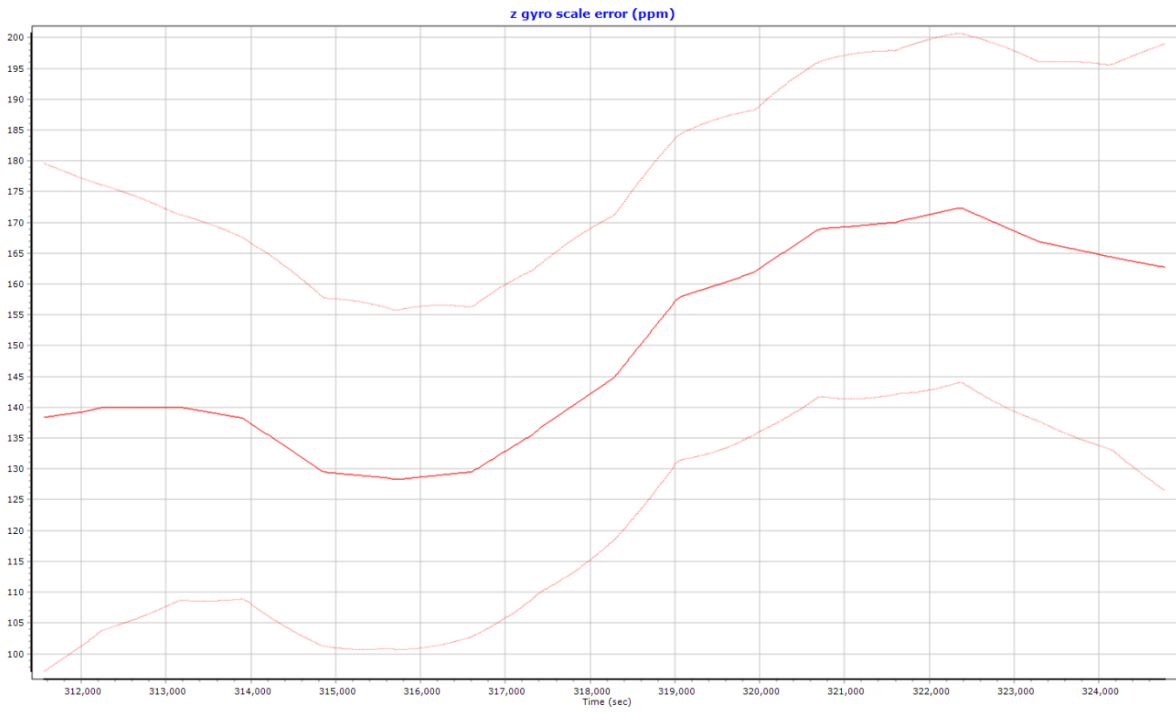
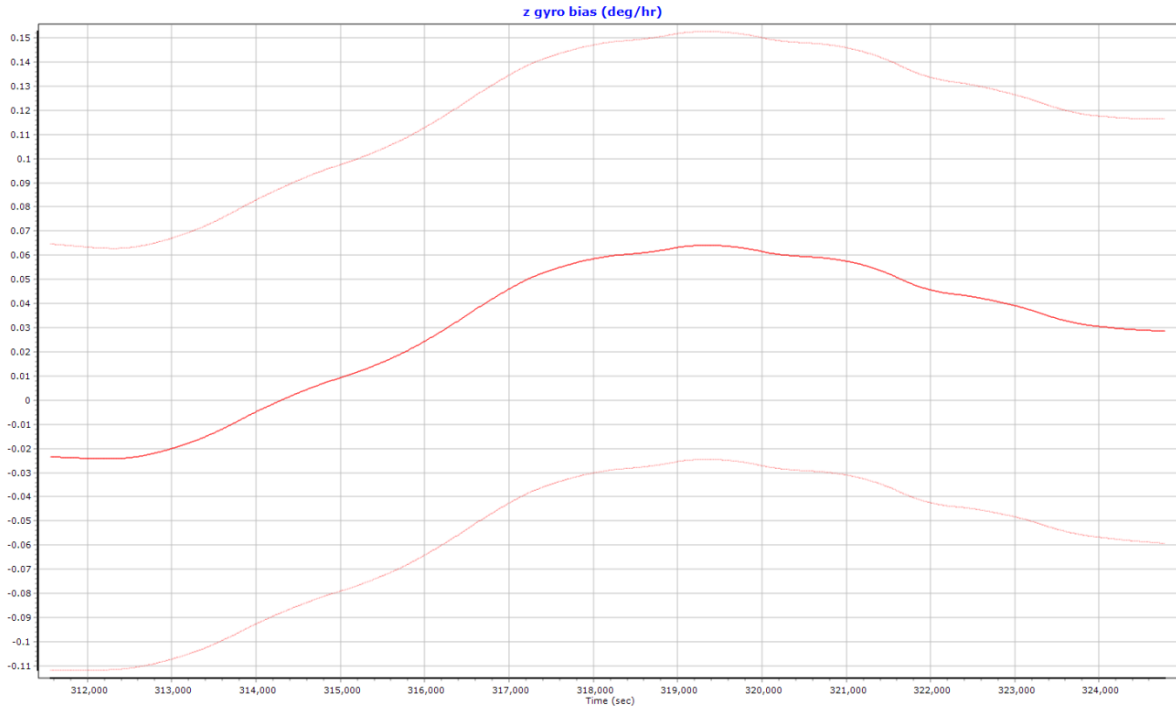






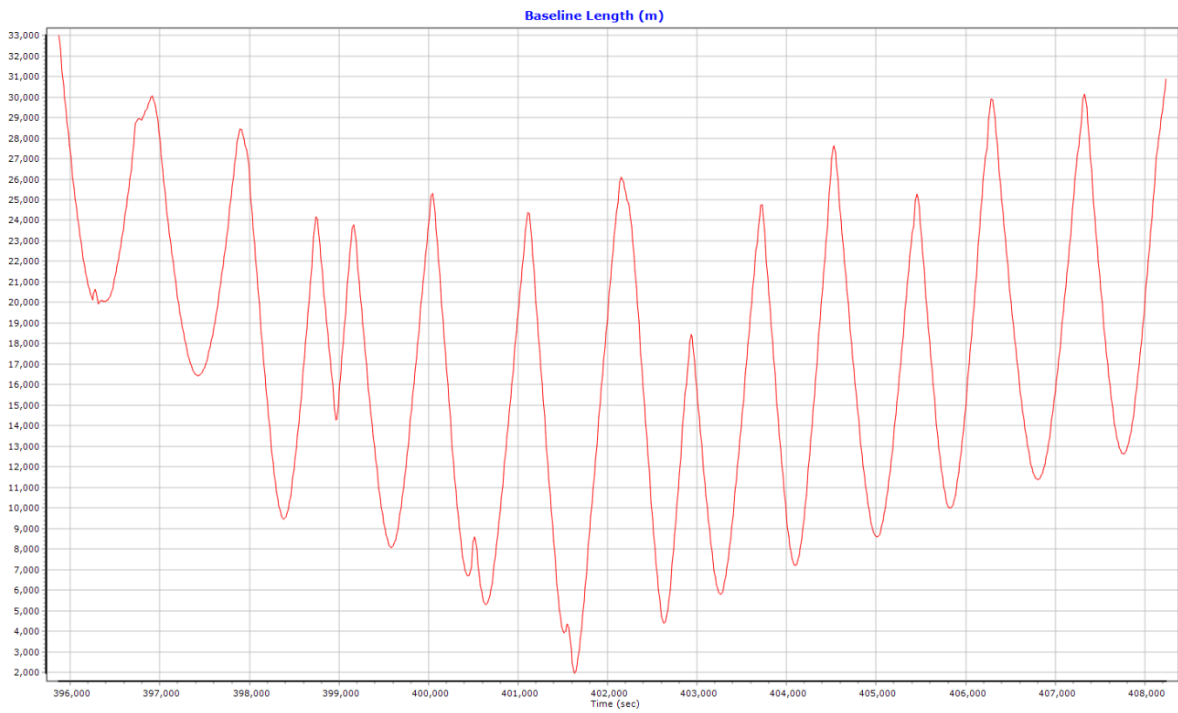
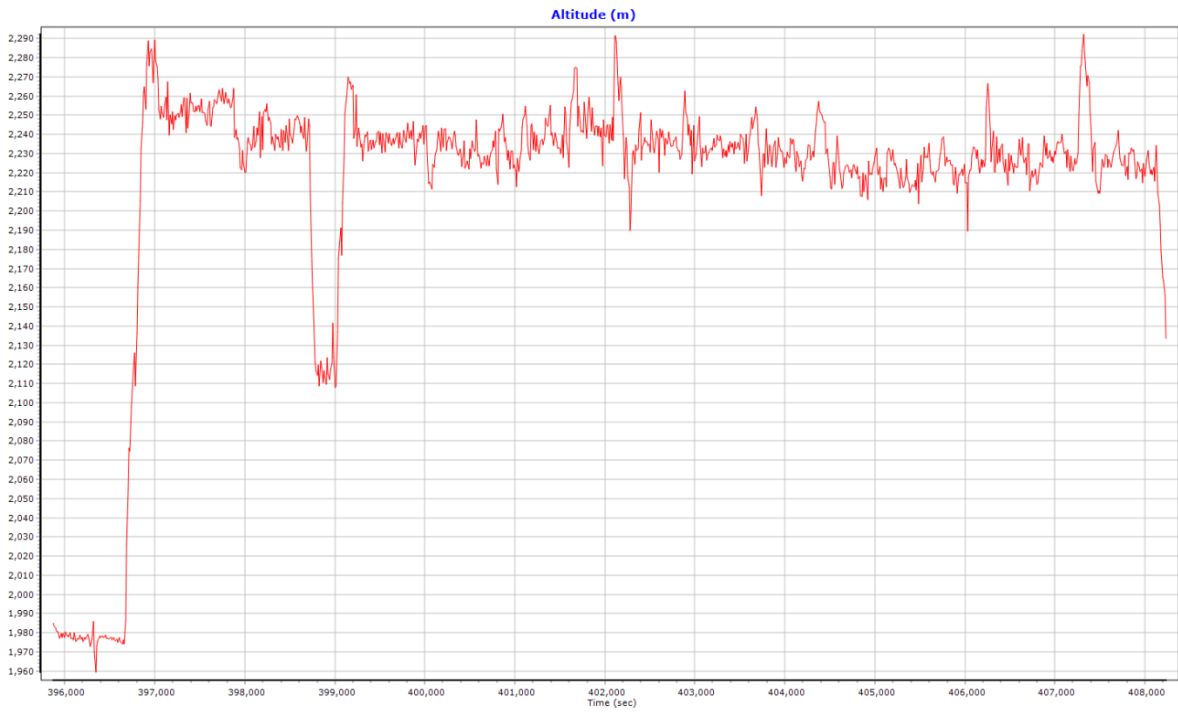


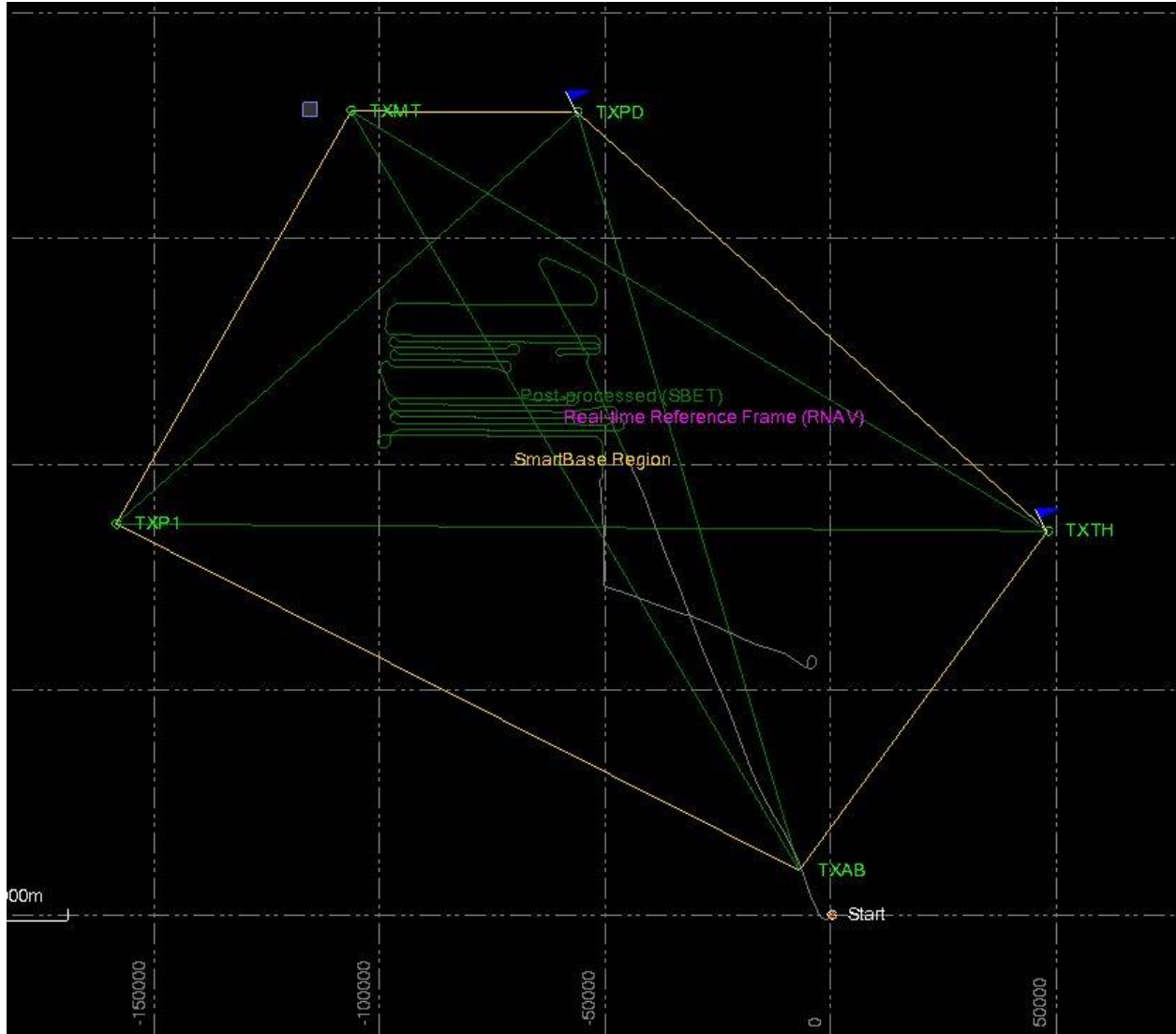




RBV18o8oB

RBV18081A







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:

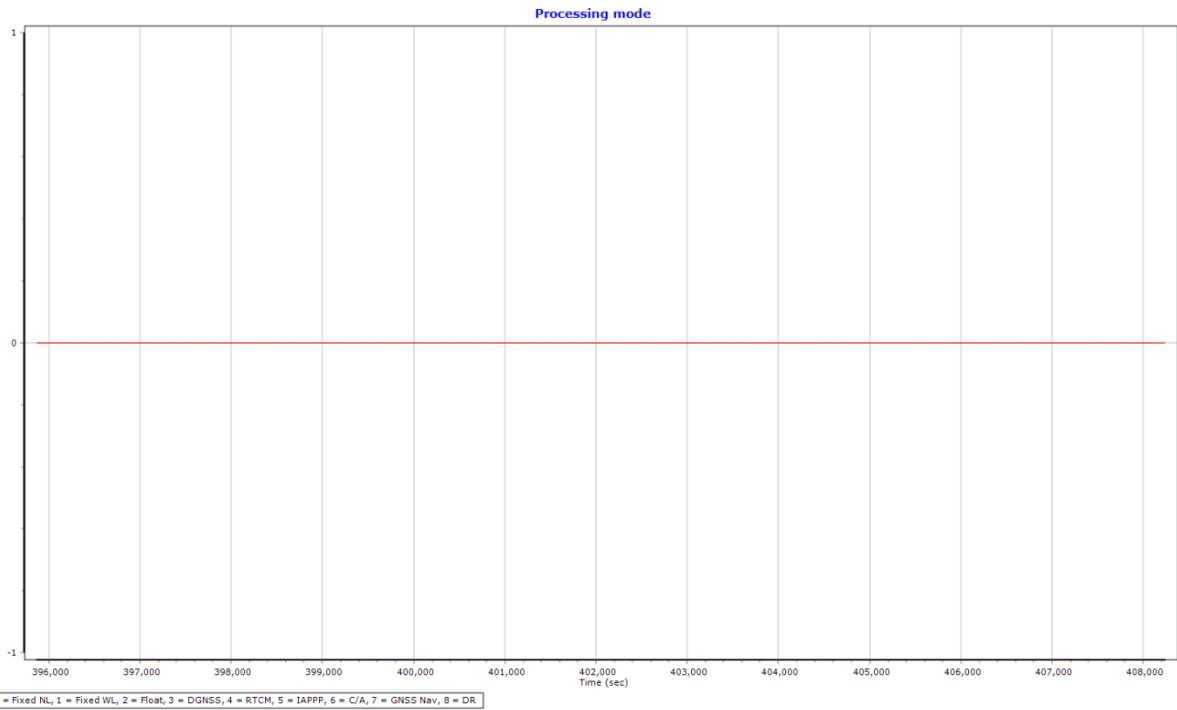
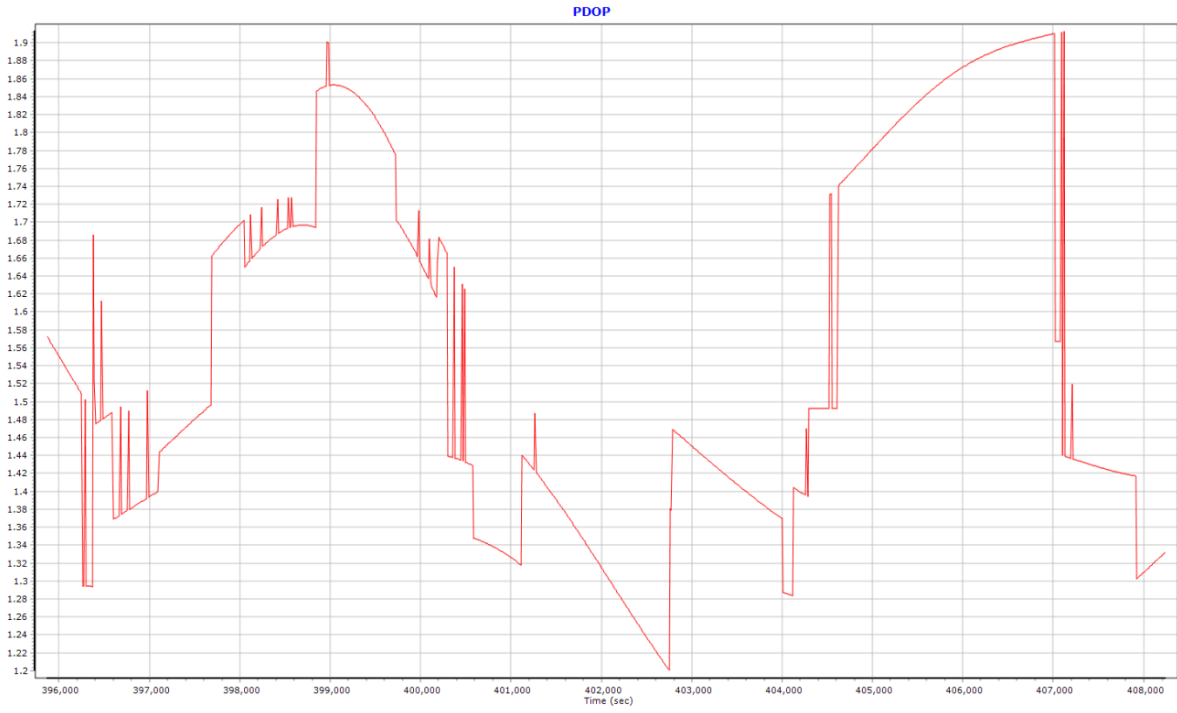
Z:

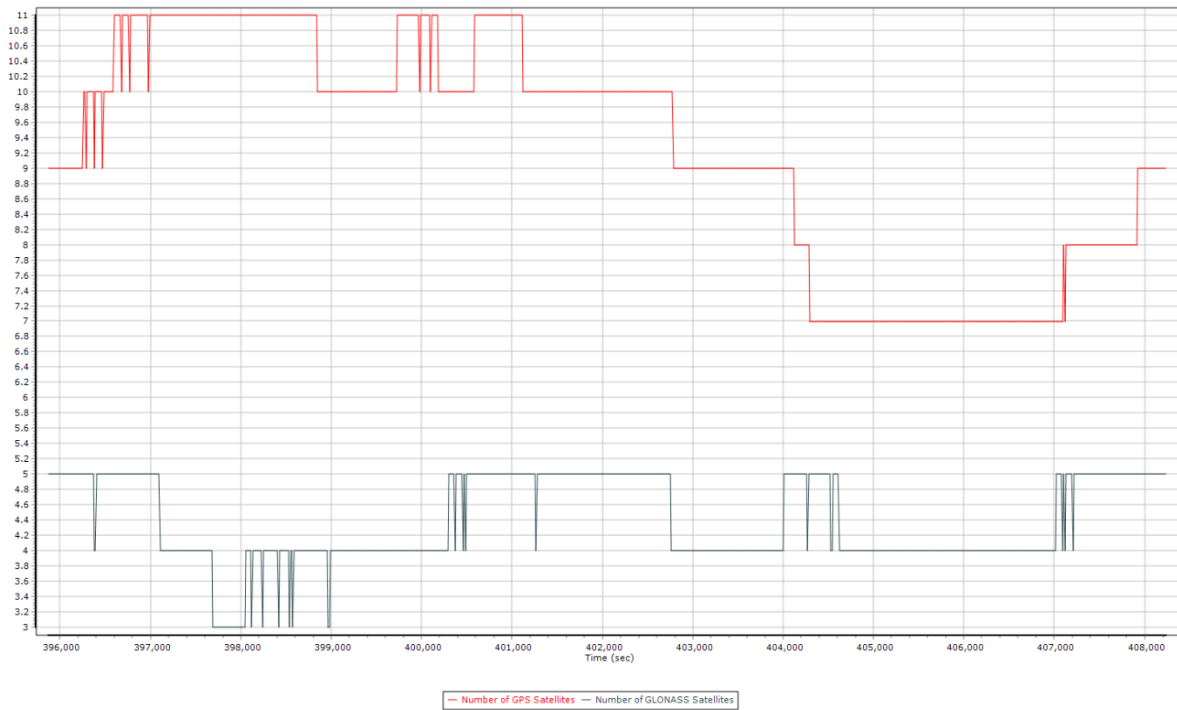
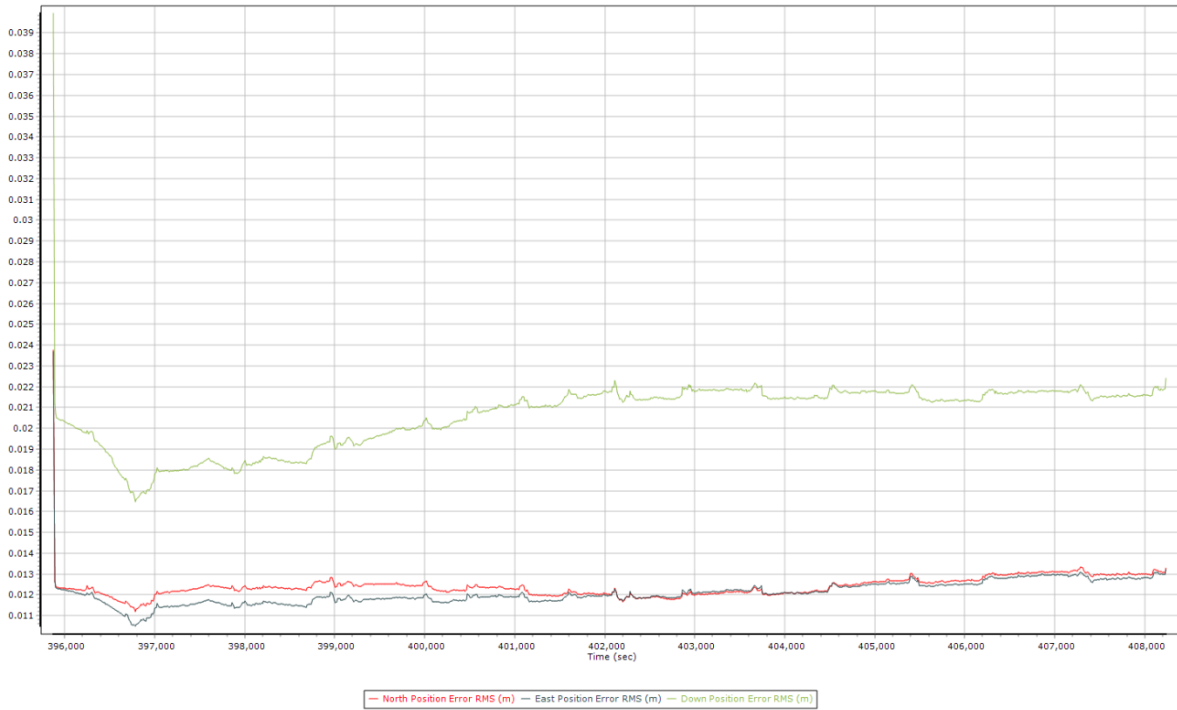
Standard Deviation

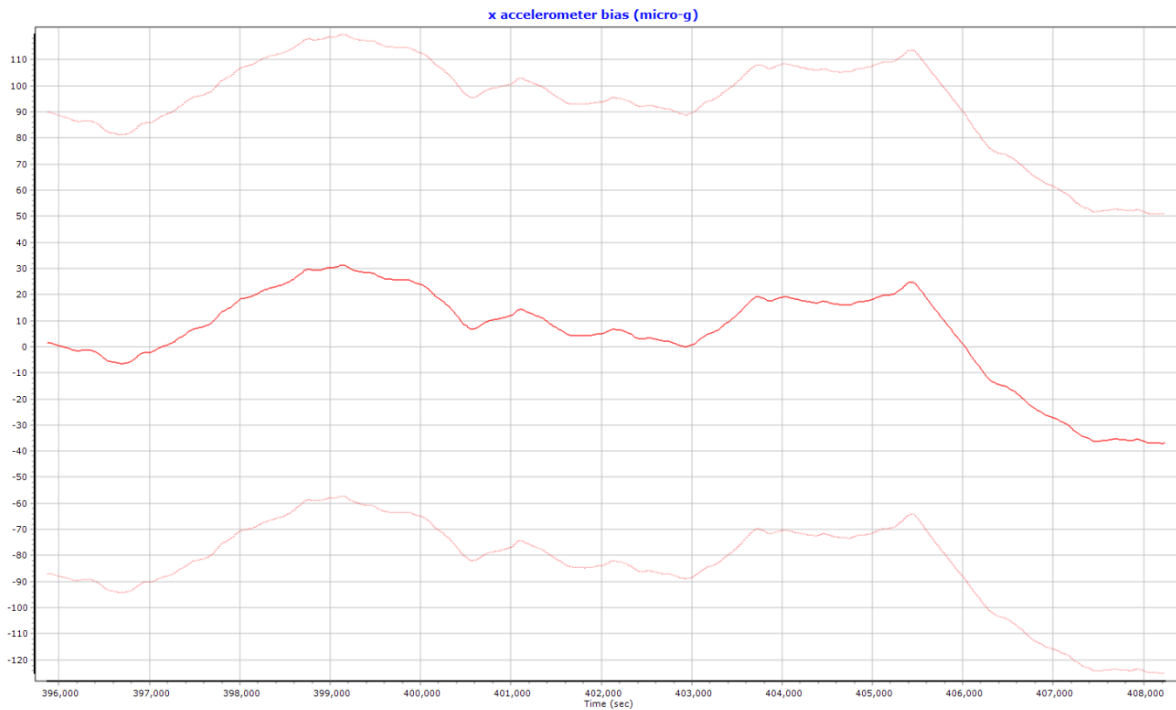
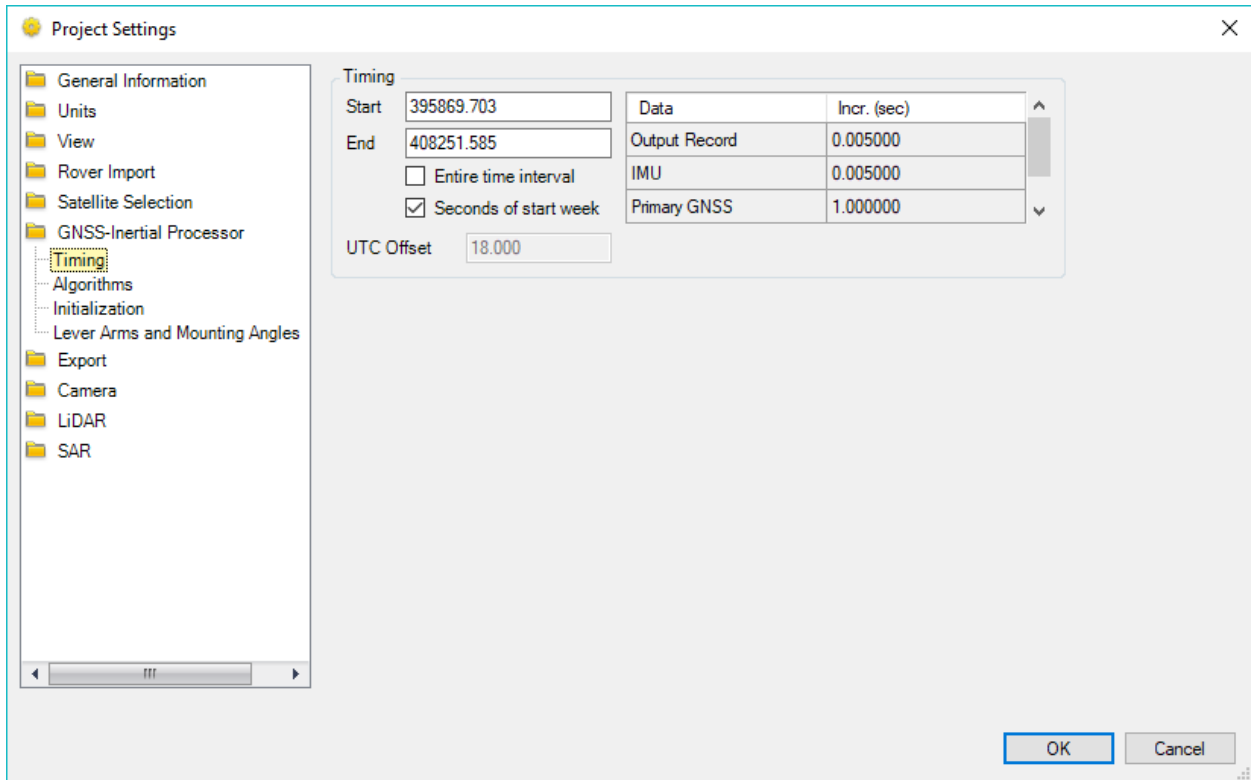
<3cm 10cm 50cm 1m 10m

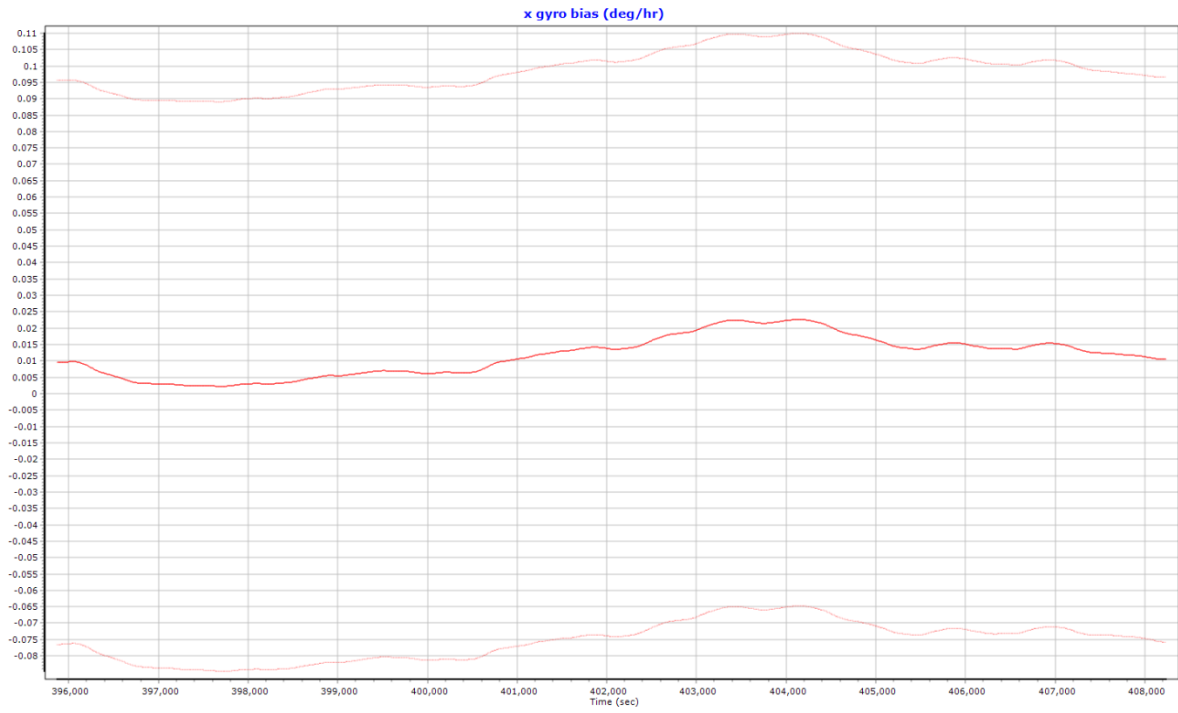
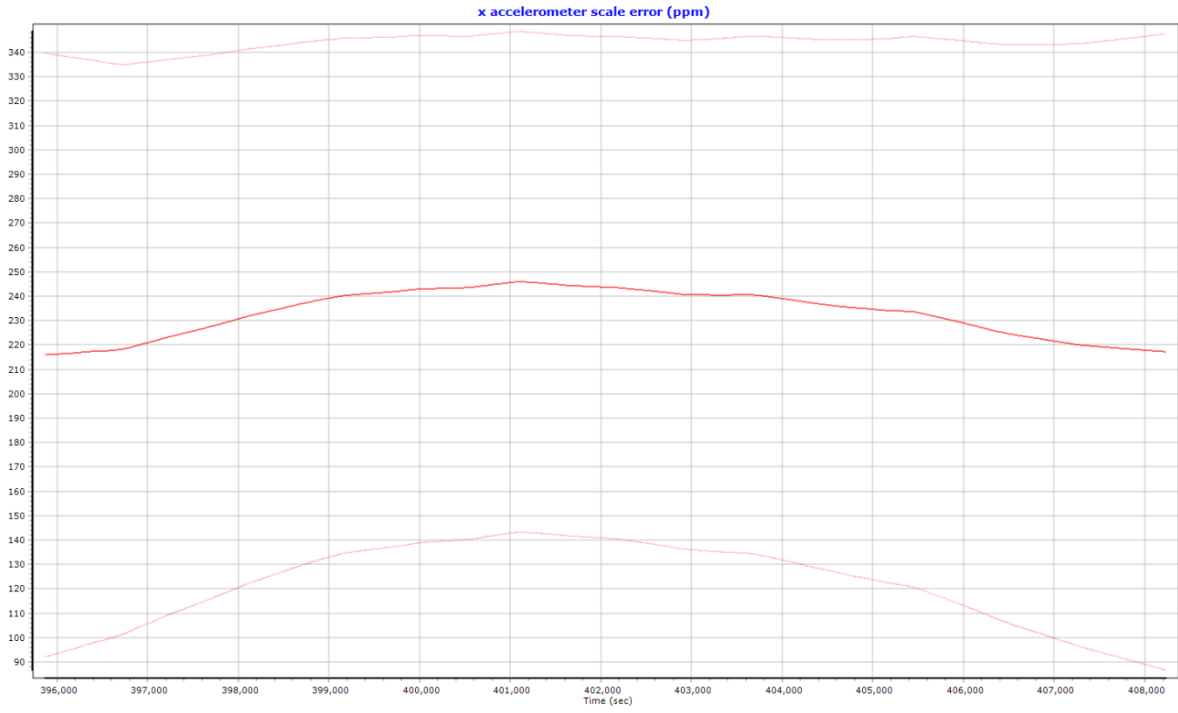
Measurements are to the stabilized platform's center of rotation with the Gimbal in the rest position.

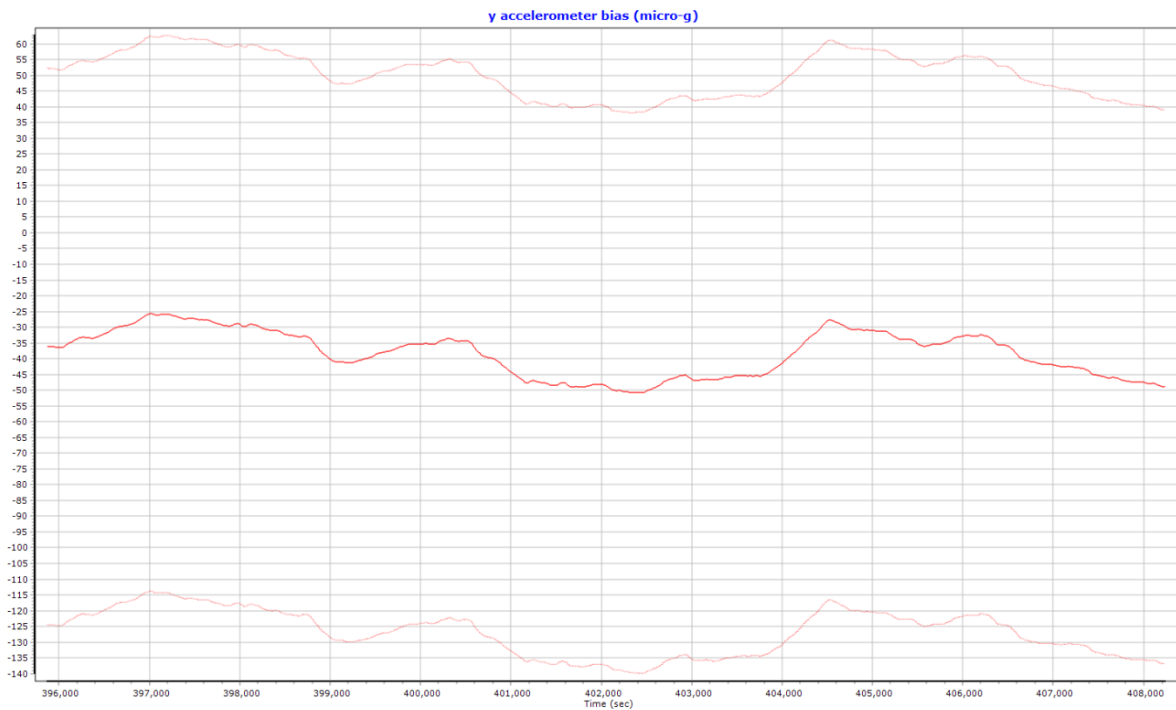
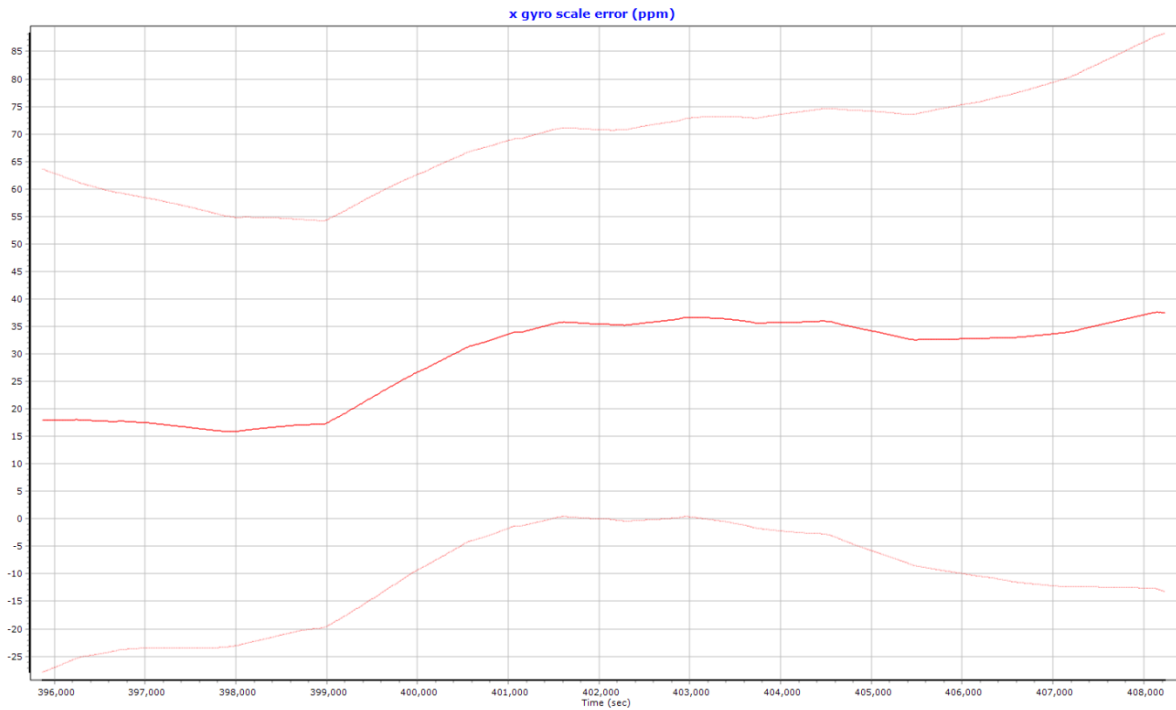
OK Cancel

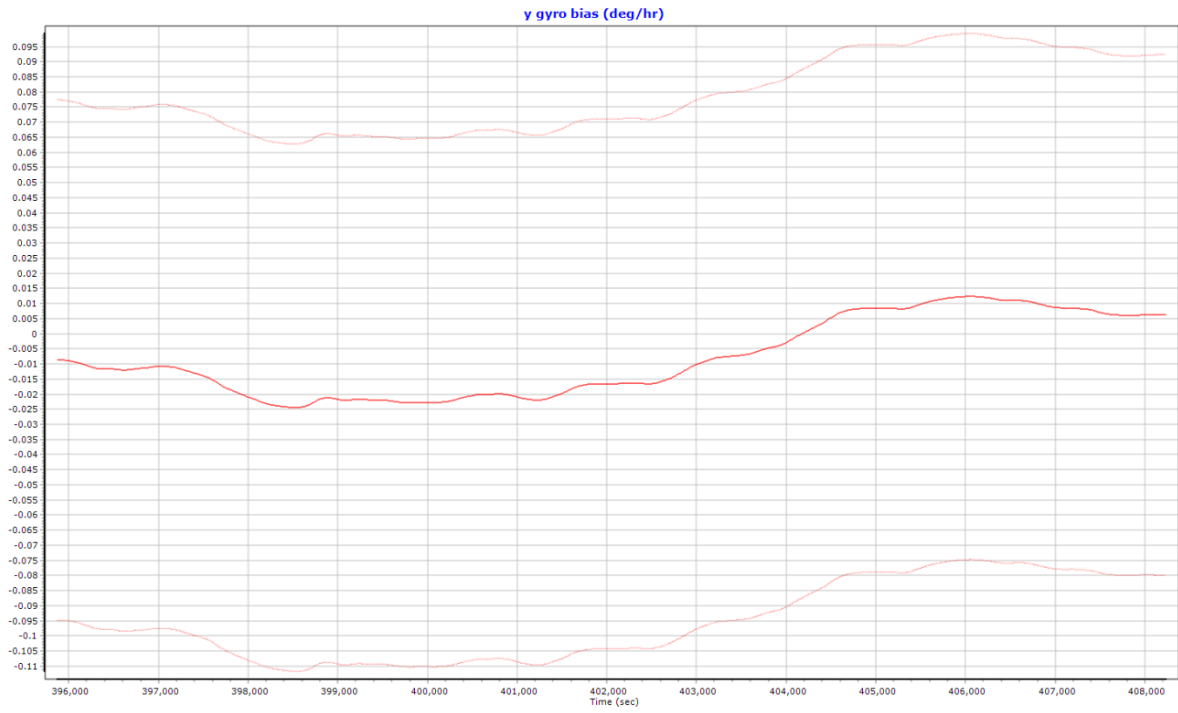
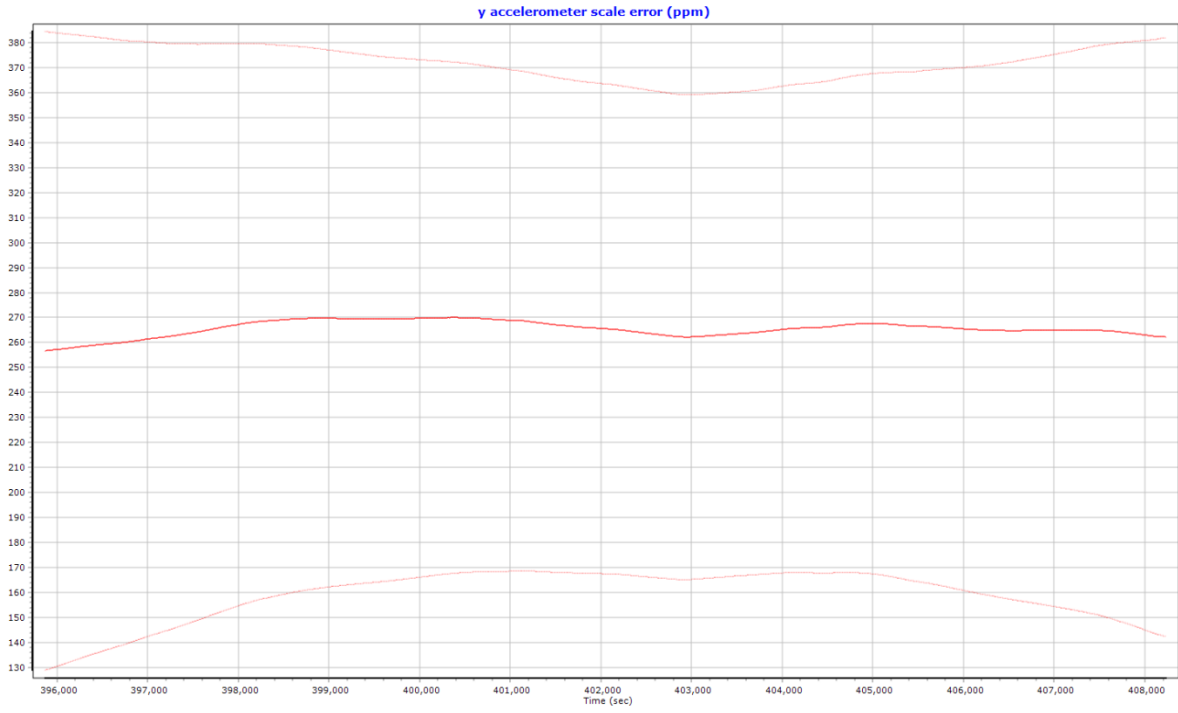


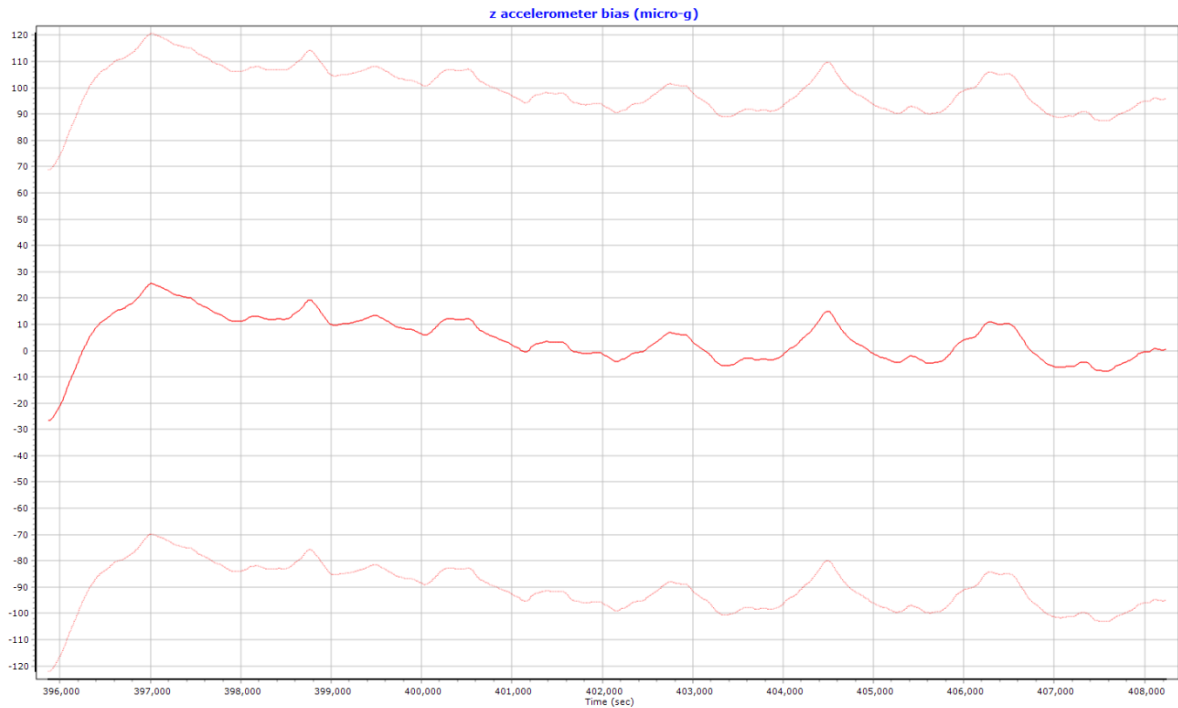
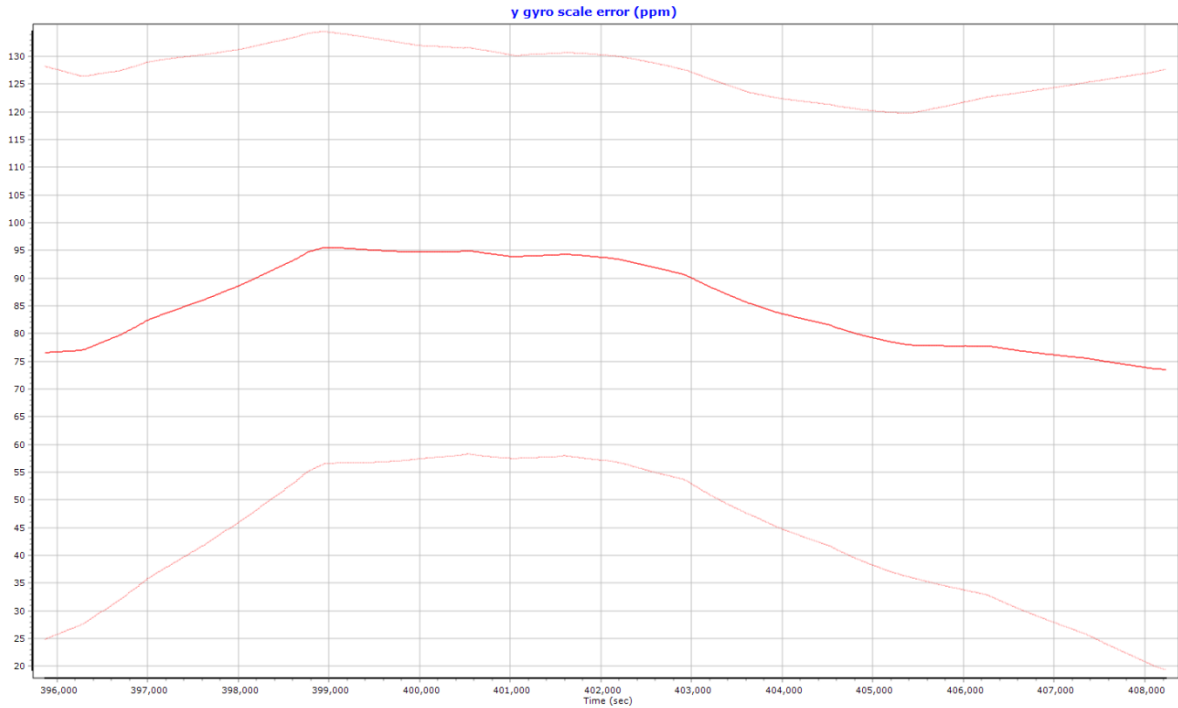


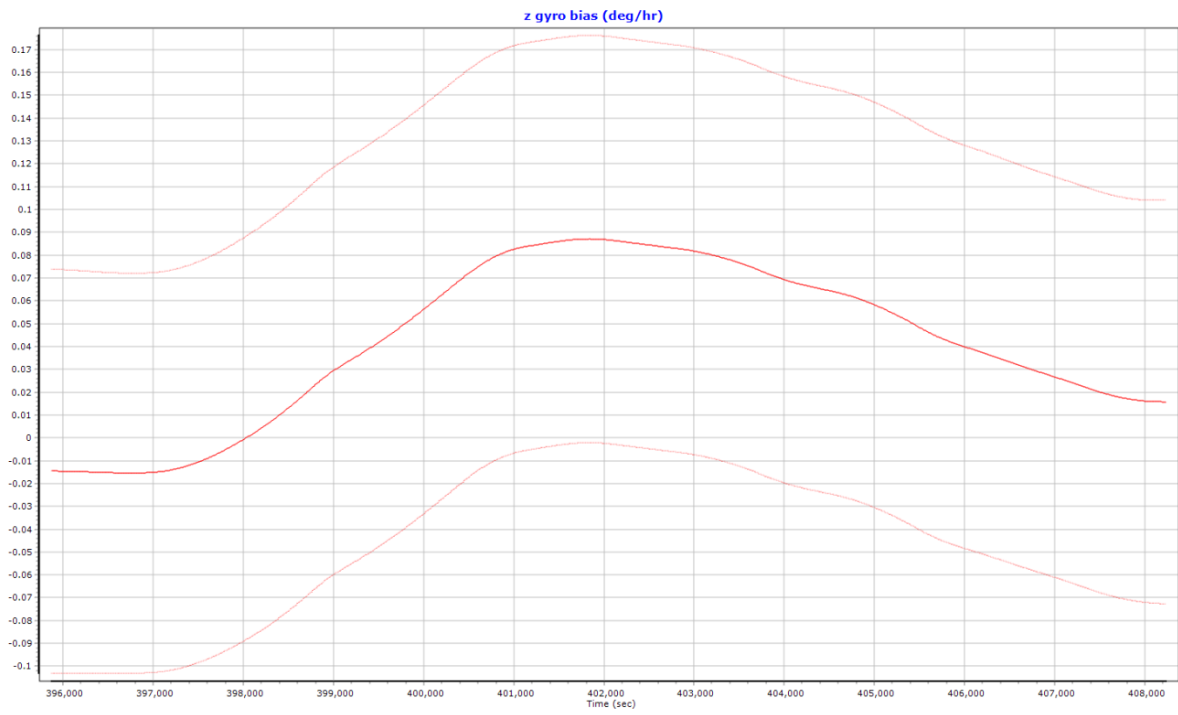
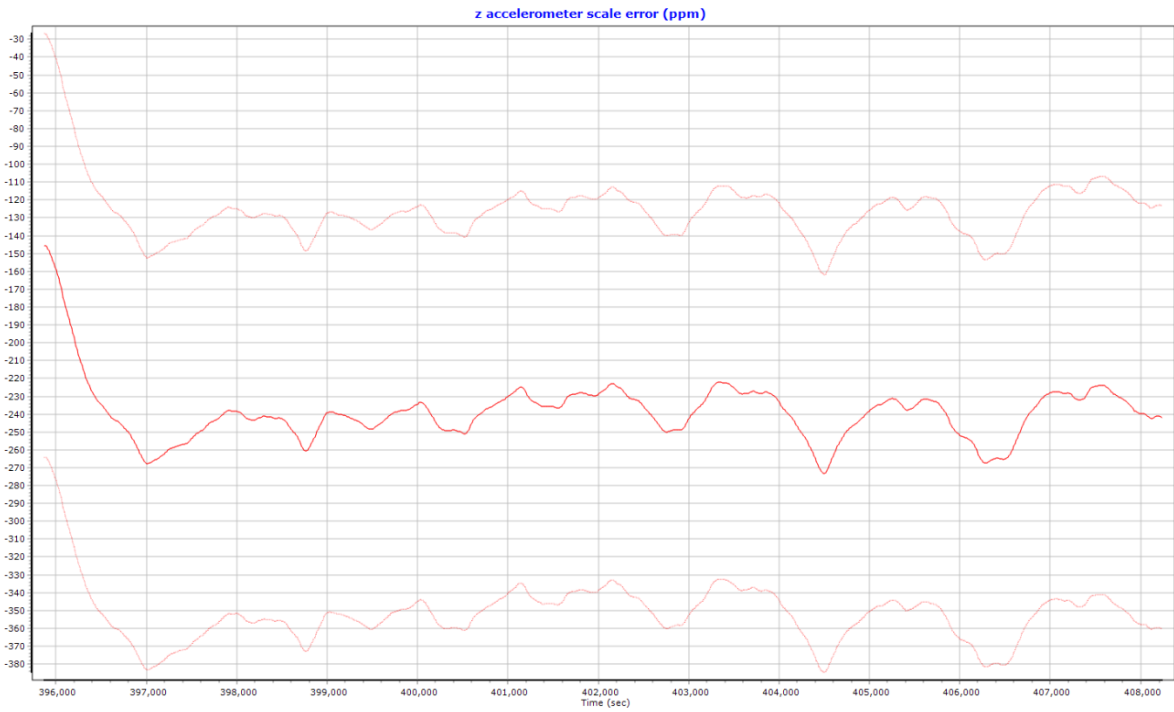


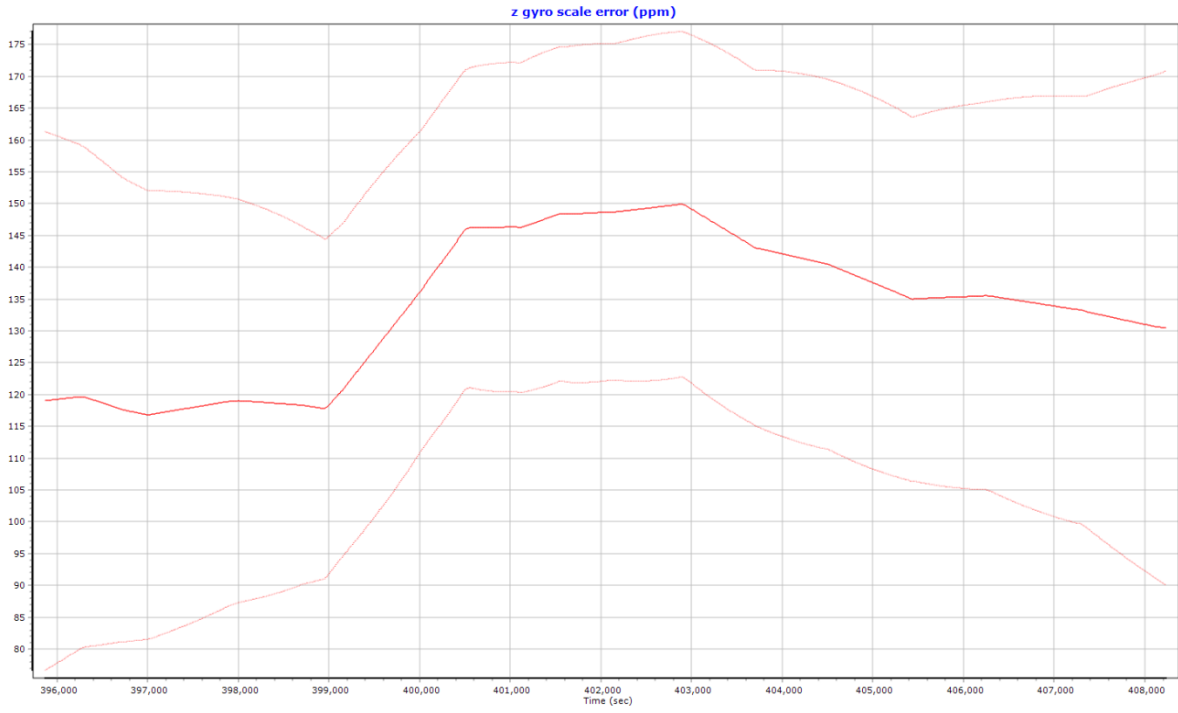




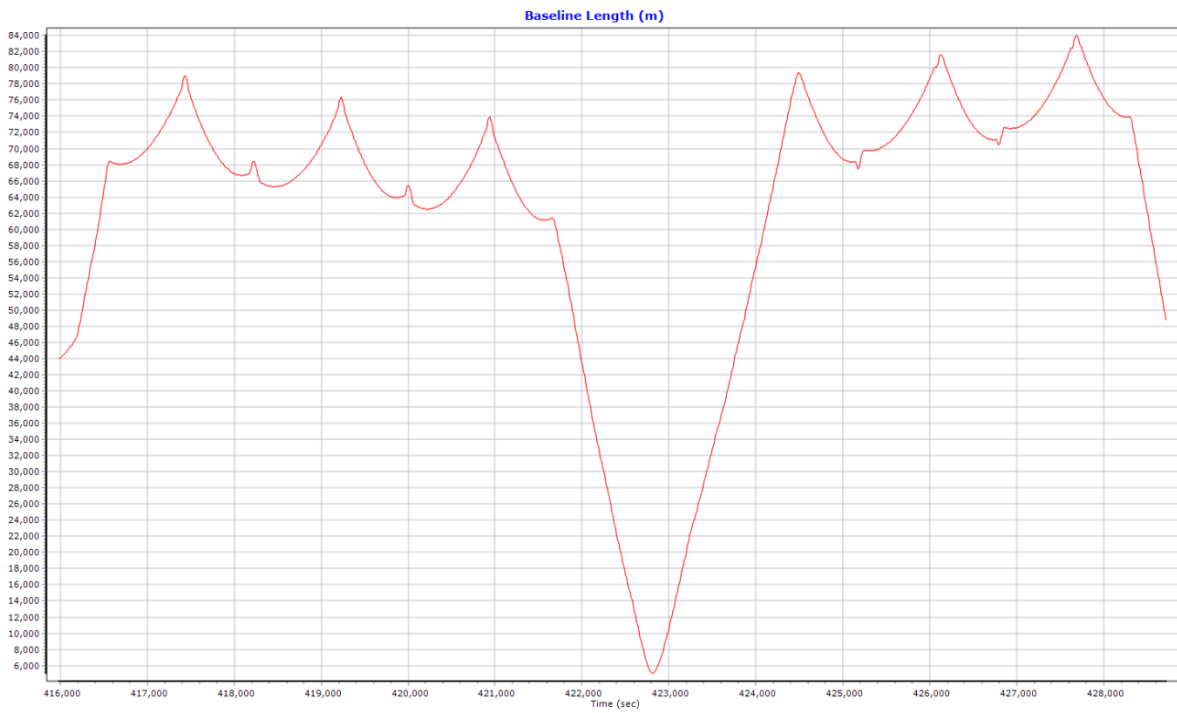
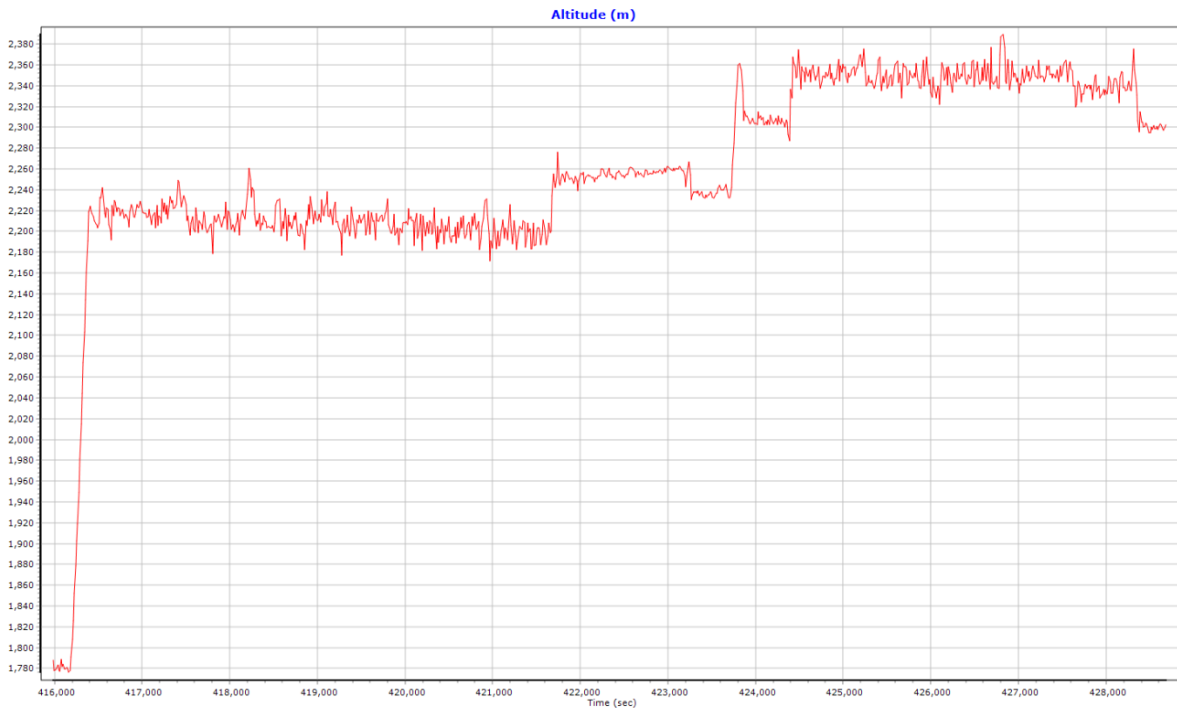


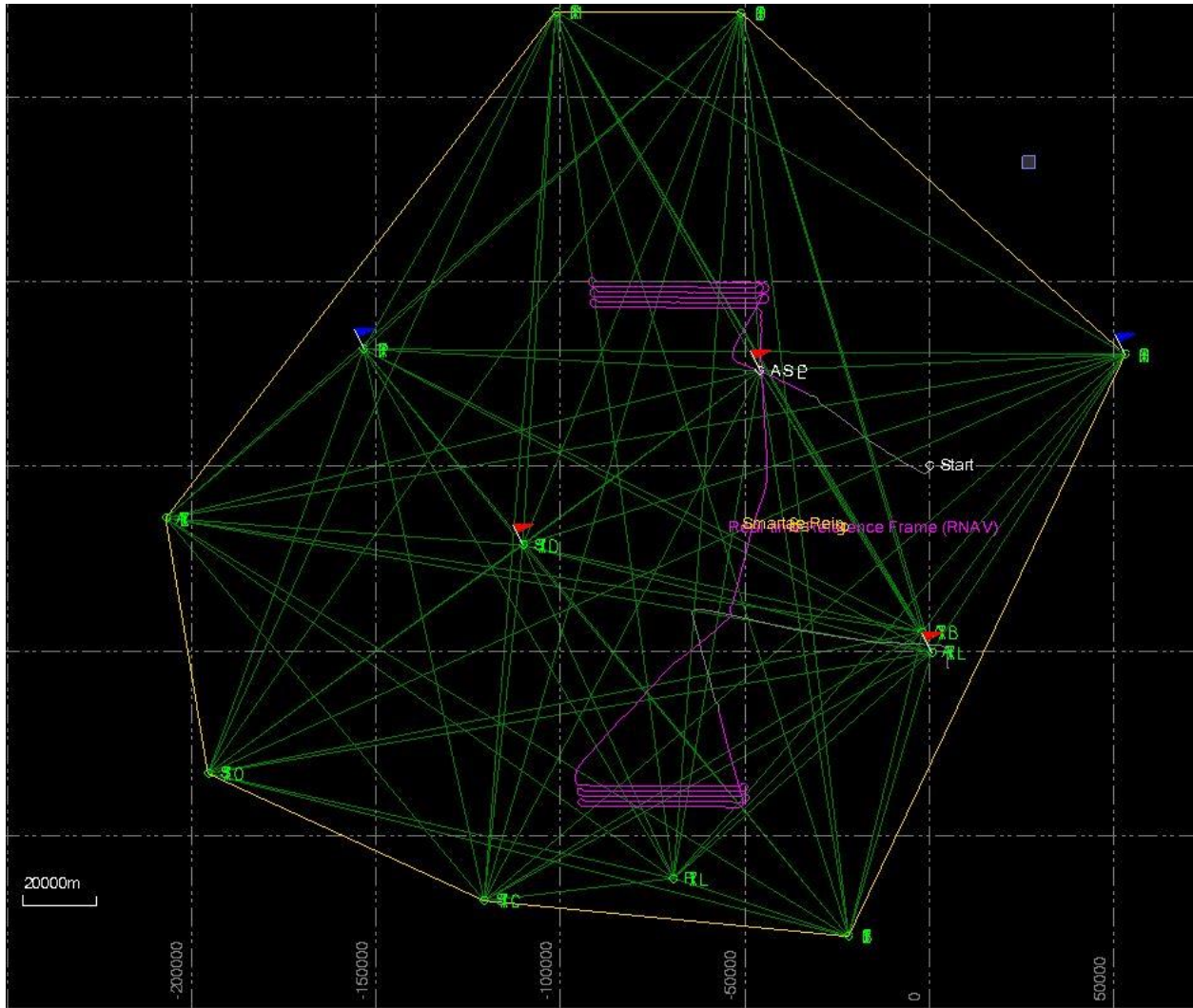


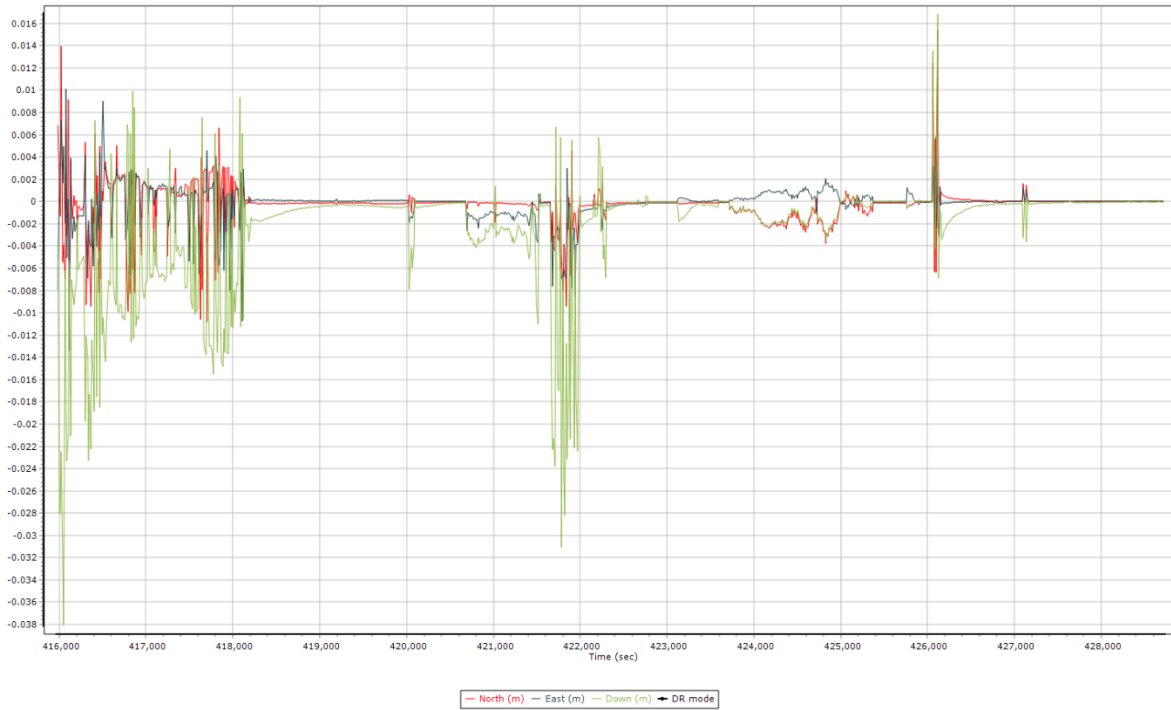




RBV18081B







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:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

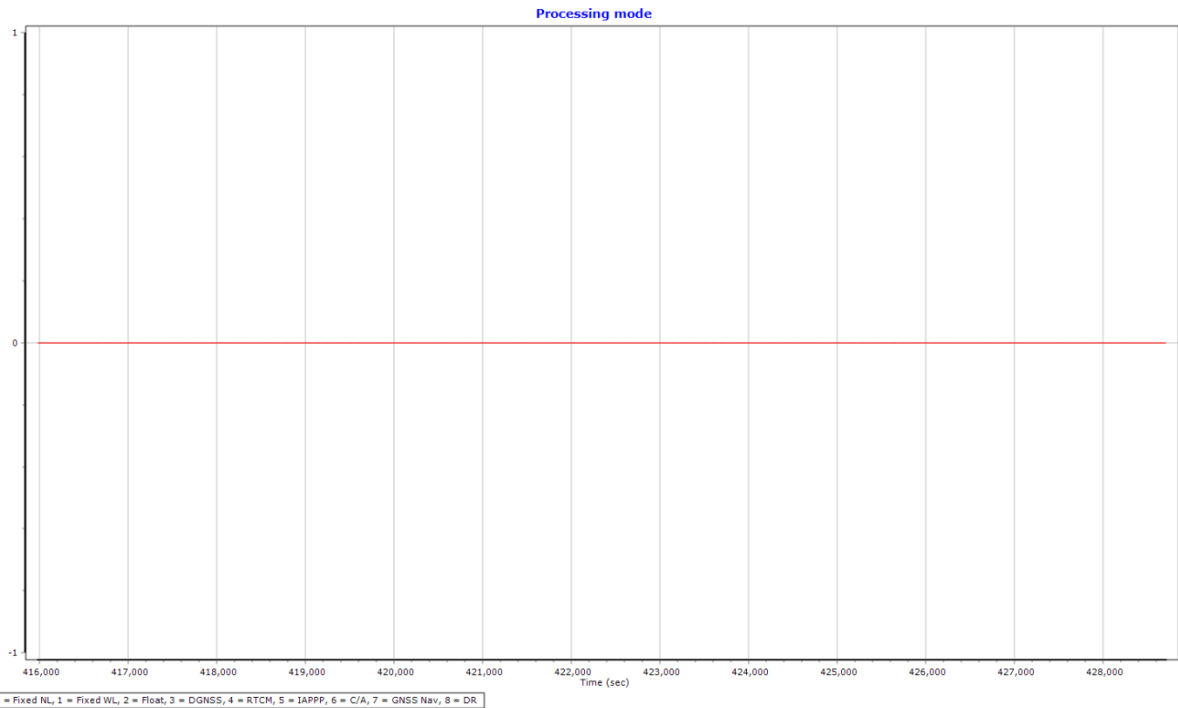
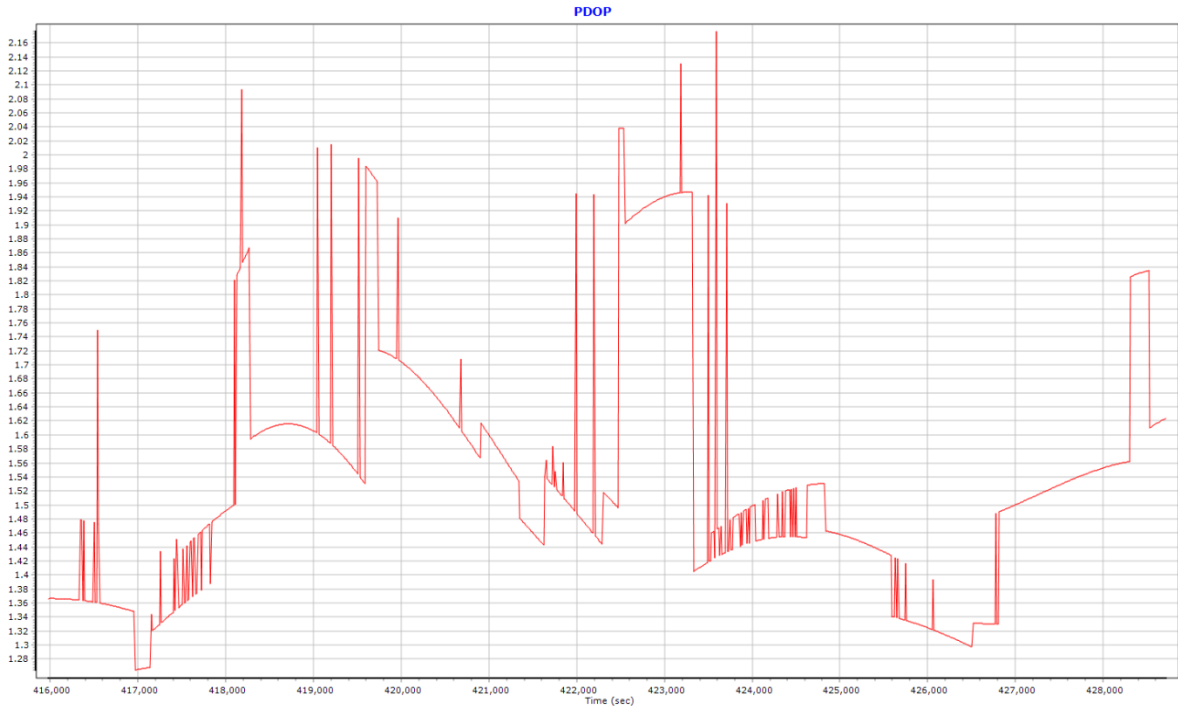
Aircraft to Stabilized Mount Mounting Angles

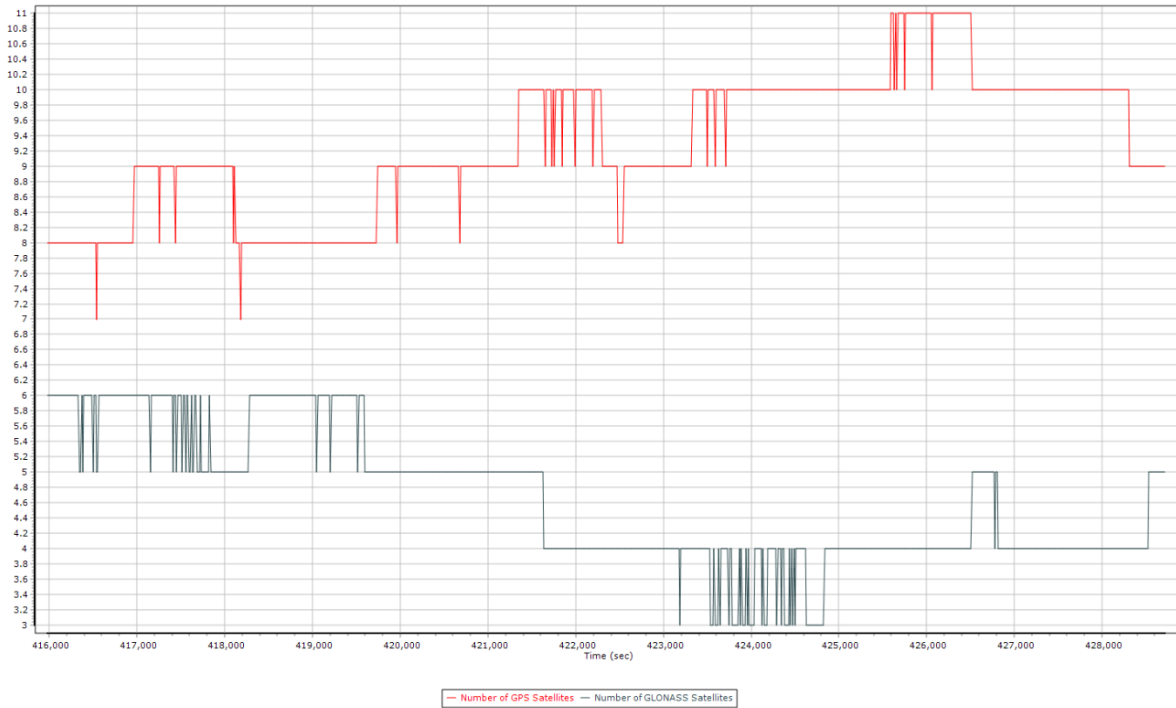
X:

Y:

Z:

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





Project Settings [X]

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

Timing

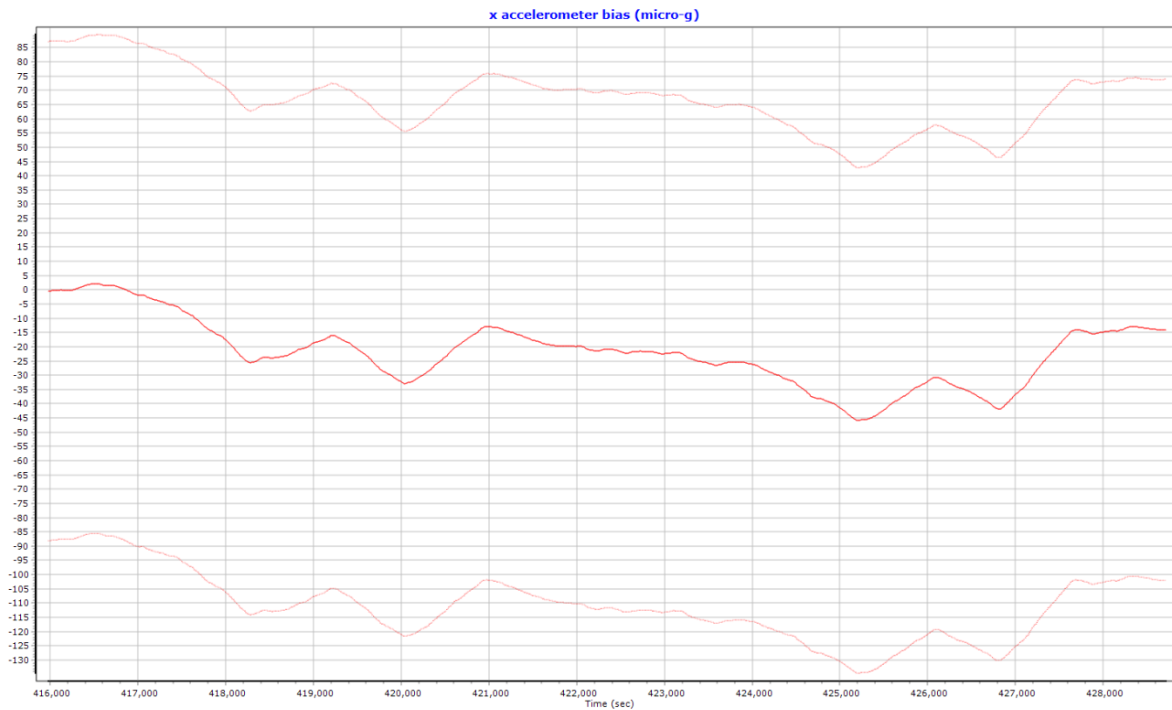
Start: 415809.971 End: 428726.013

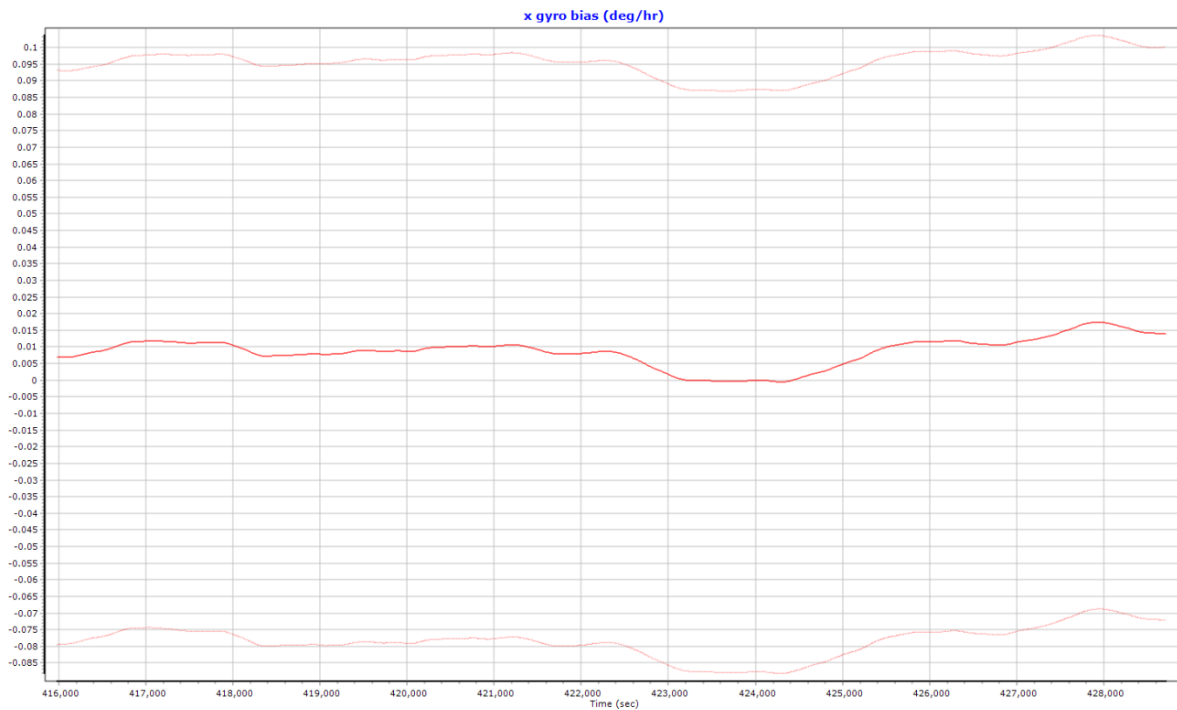
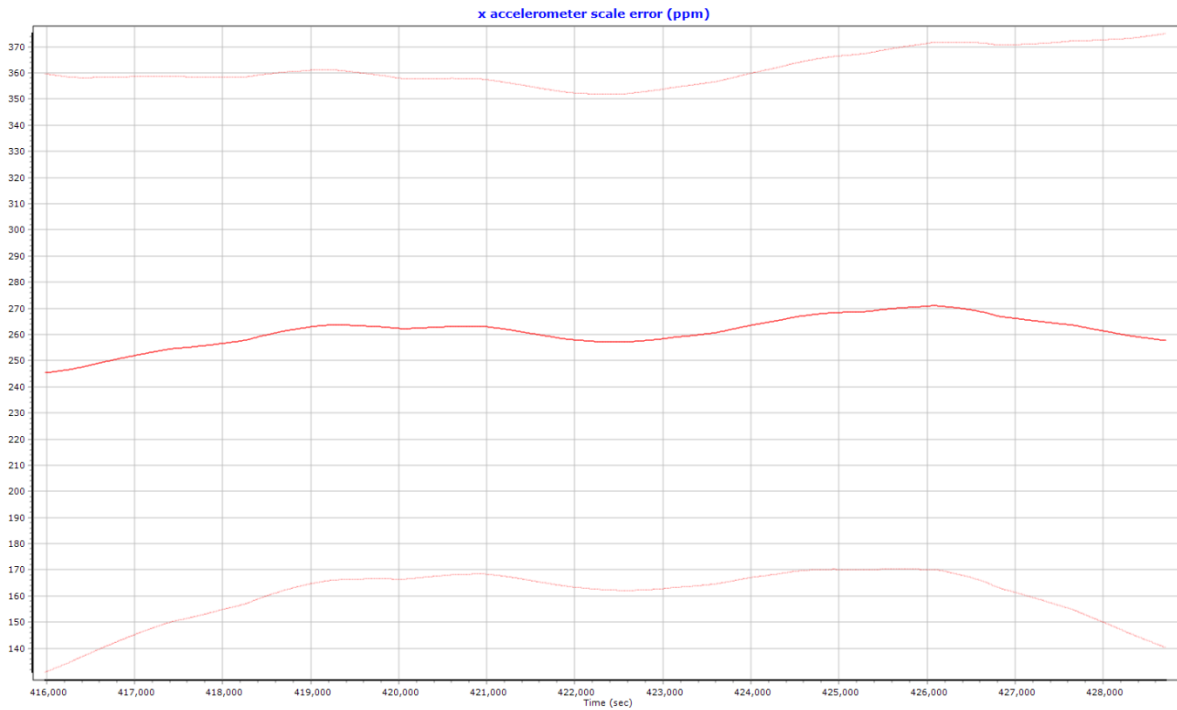
Entire time interval Seconds of start week

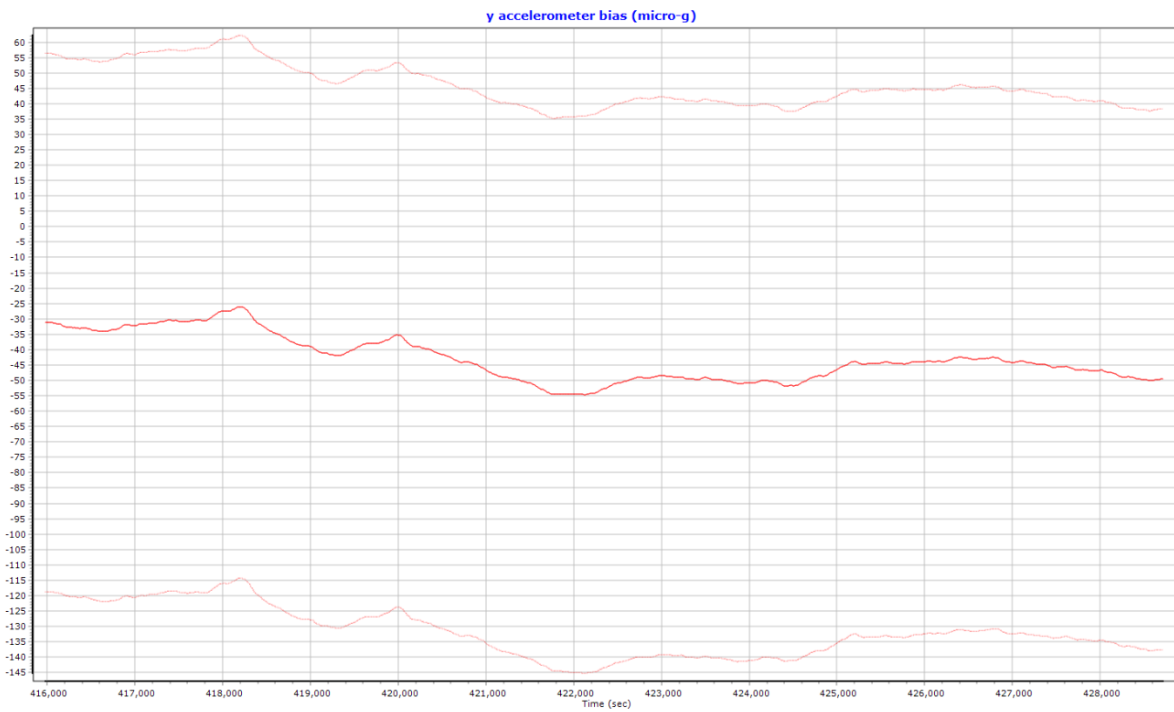
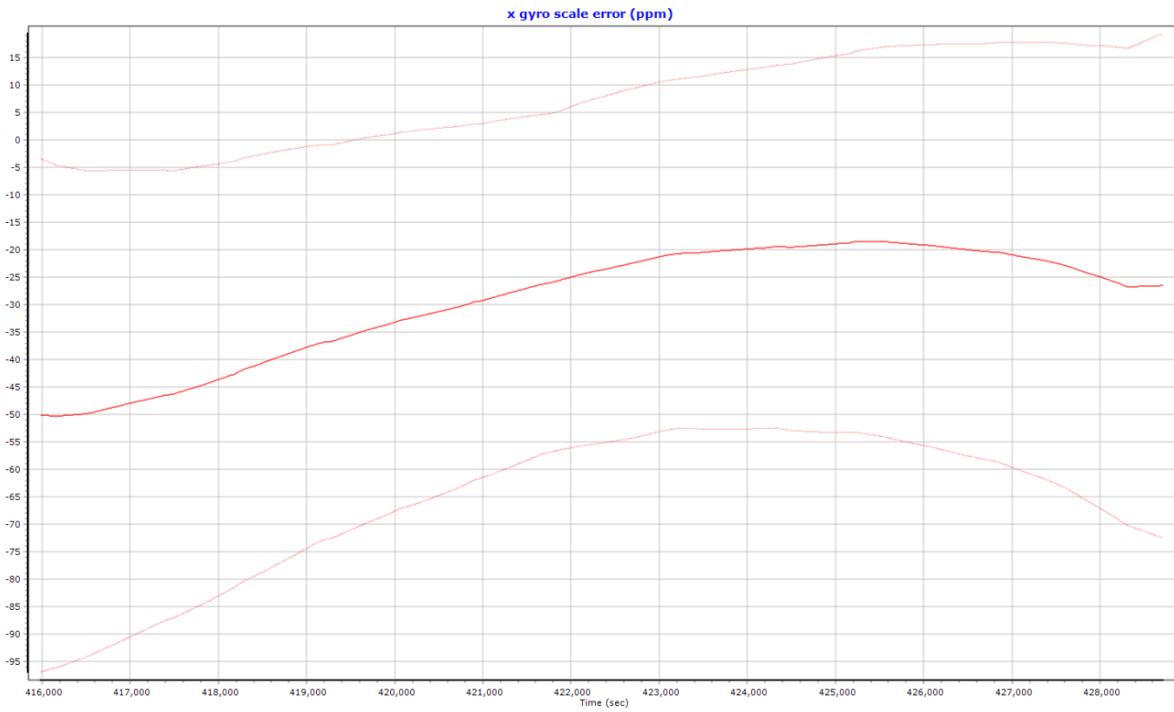
UTC Offset: 18.000

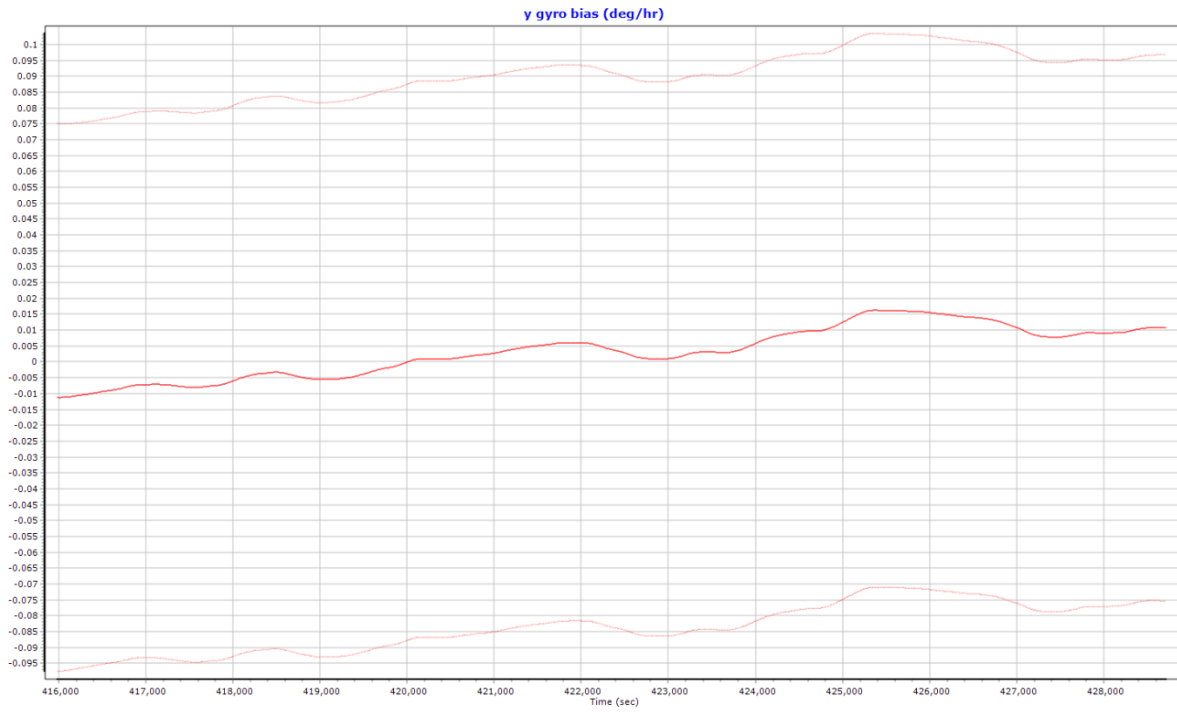
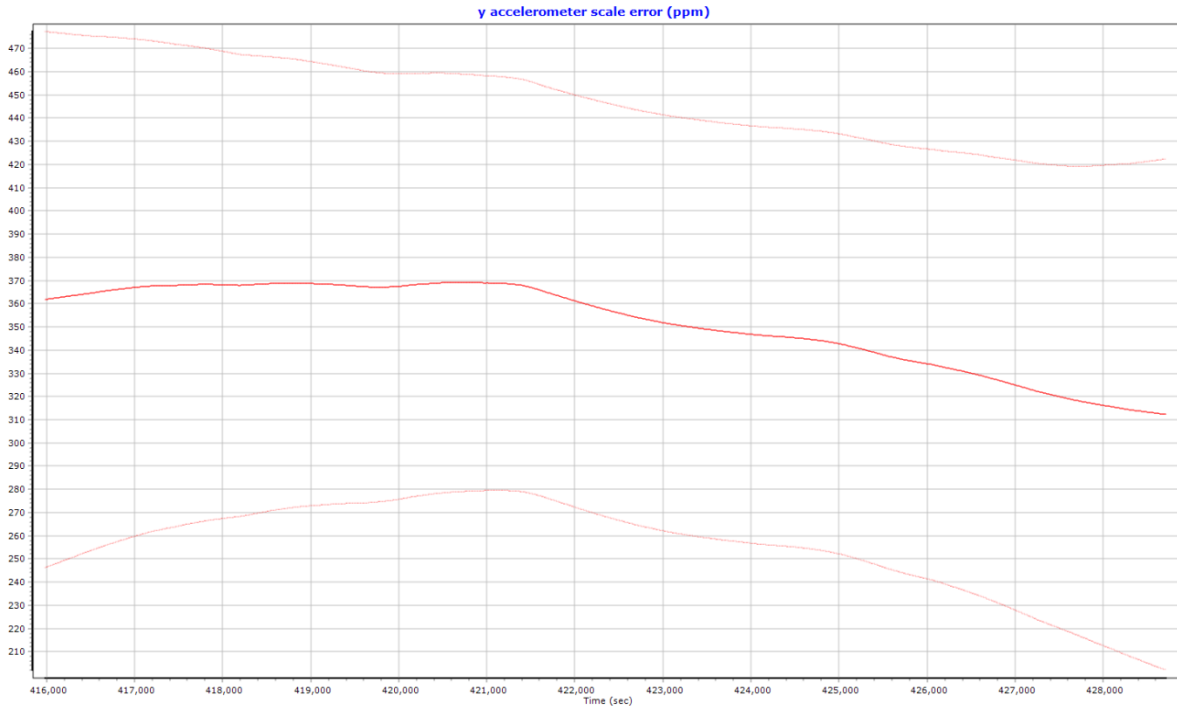
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

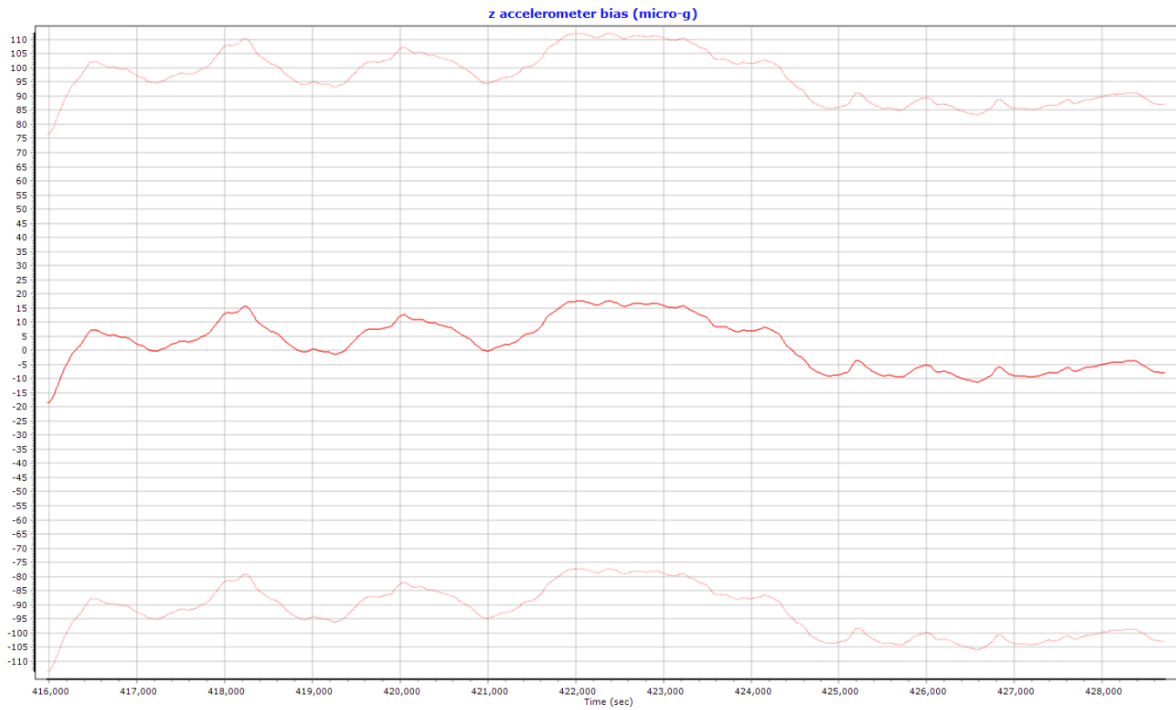
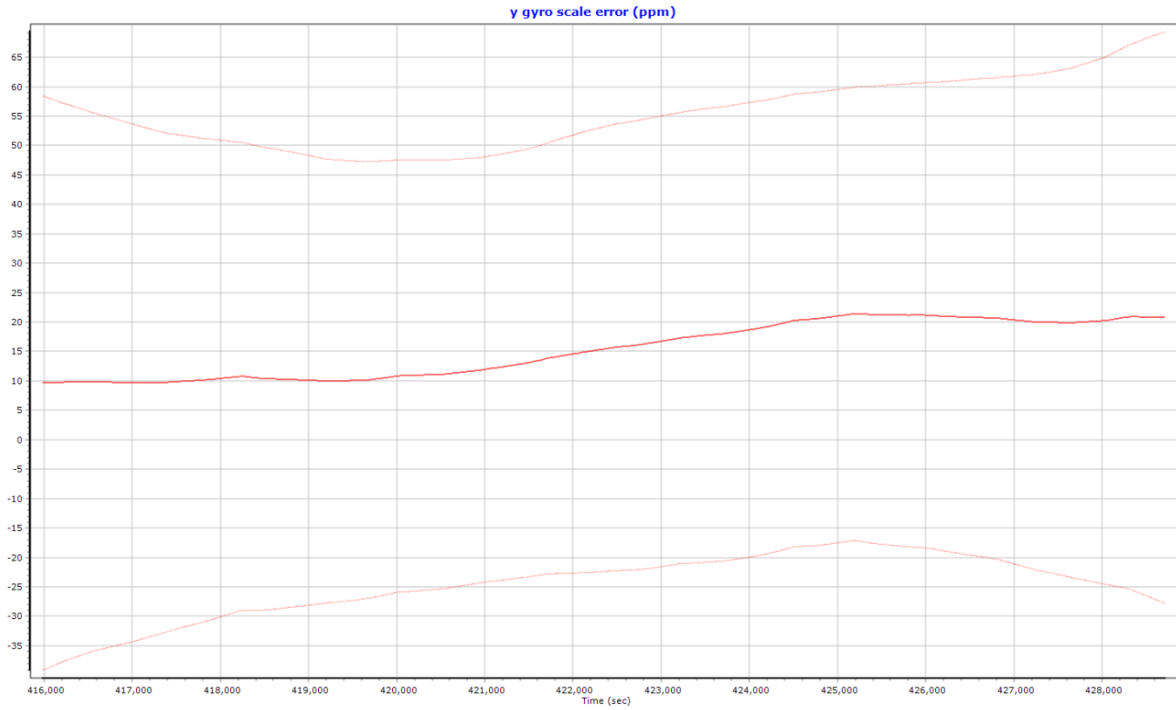
OK Cancel

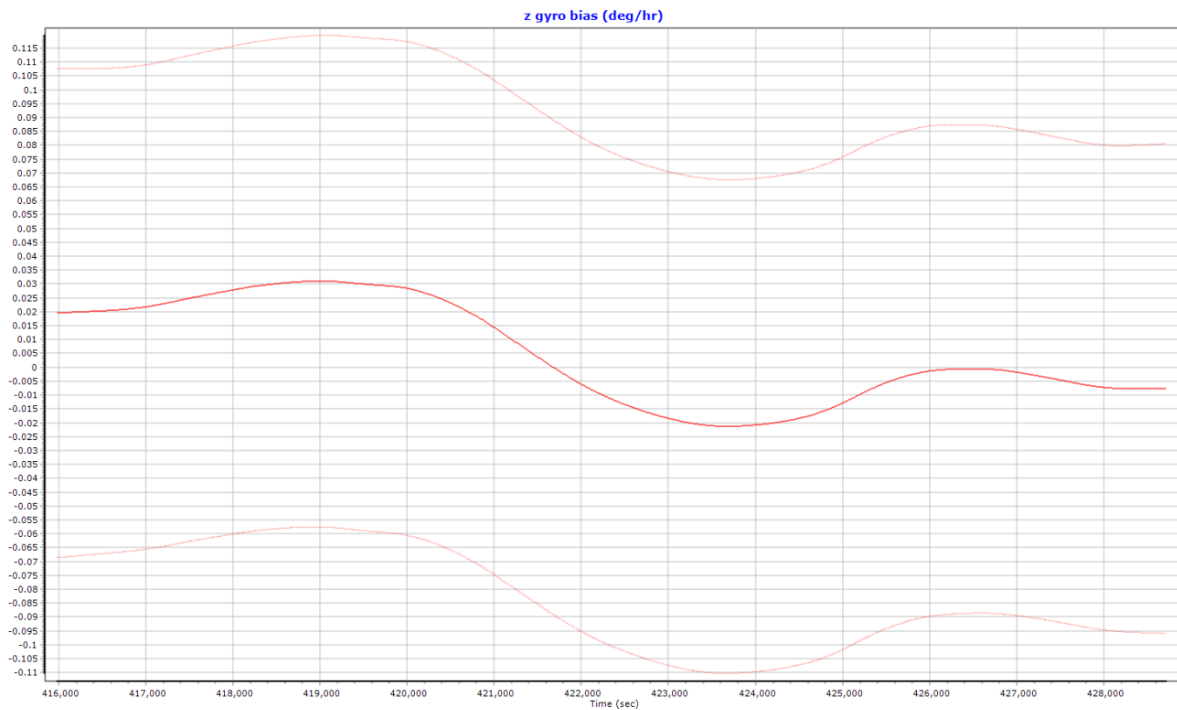
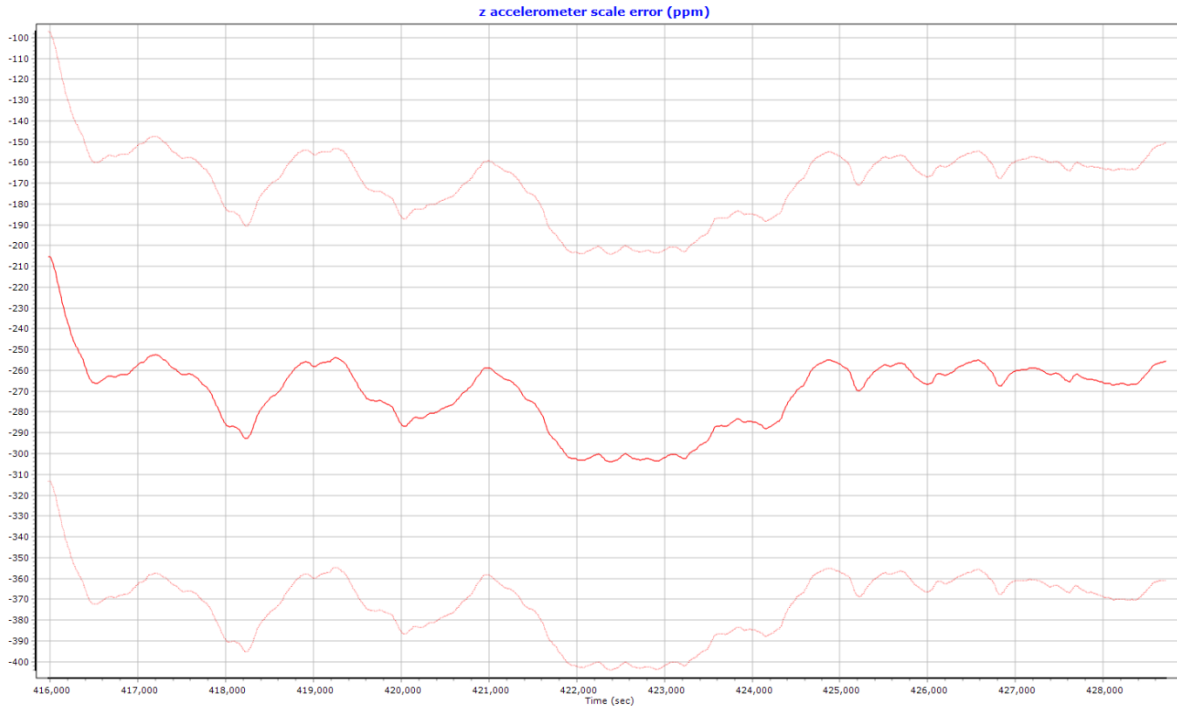


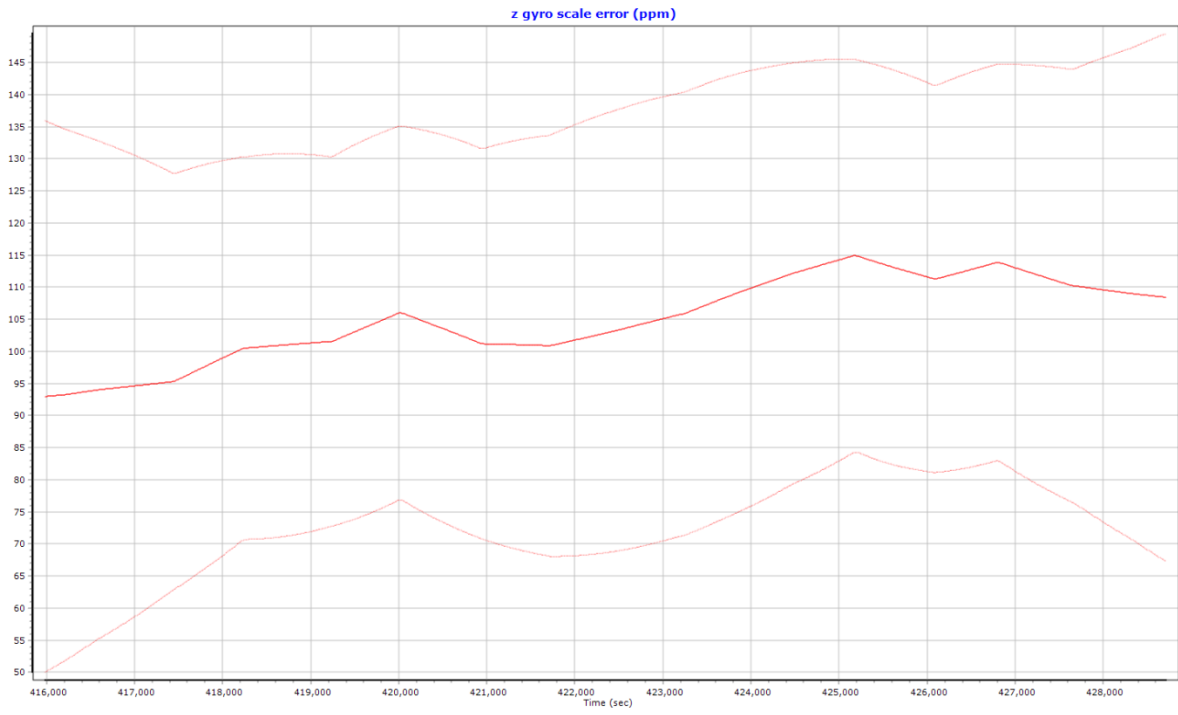




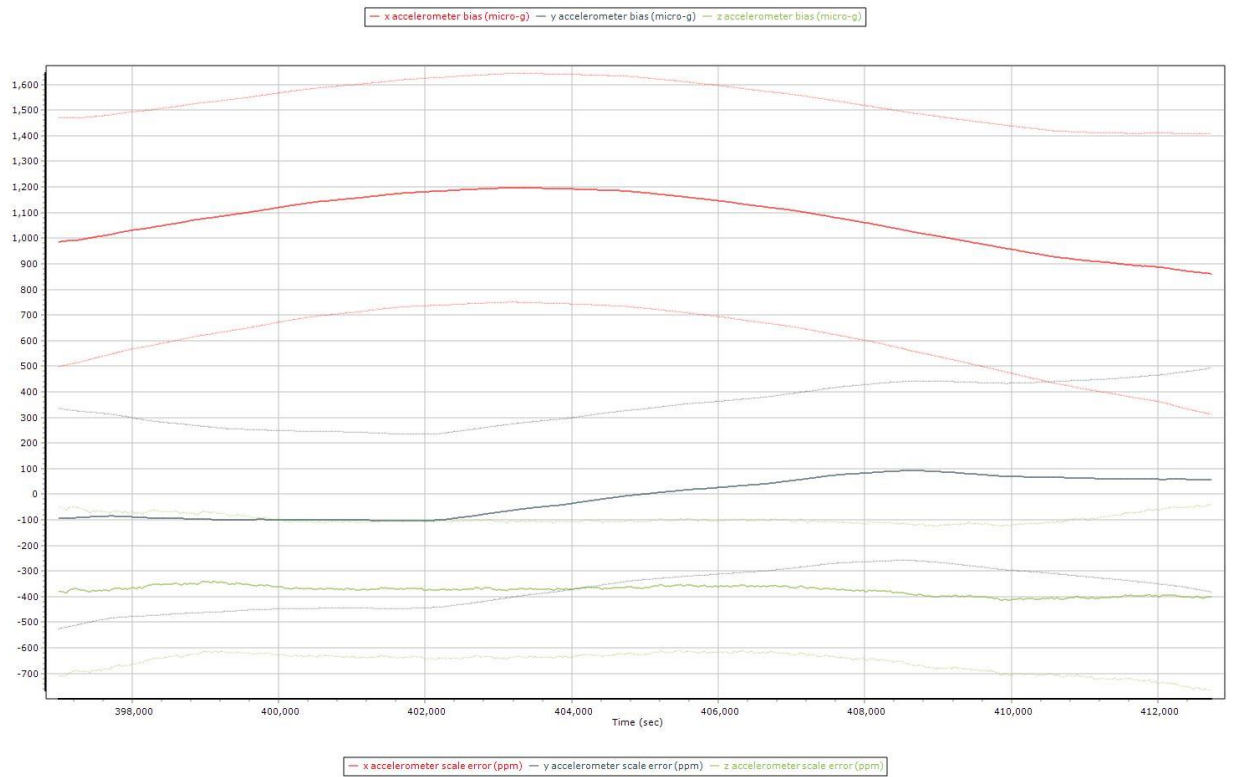
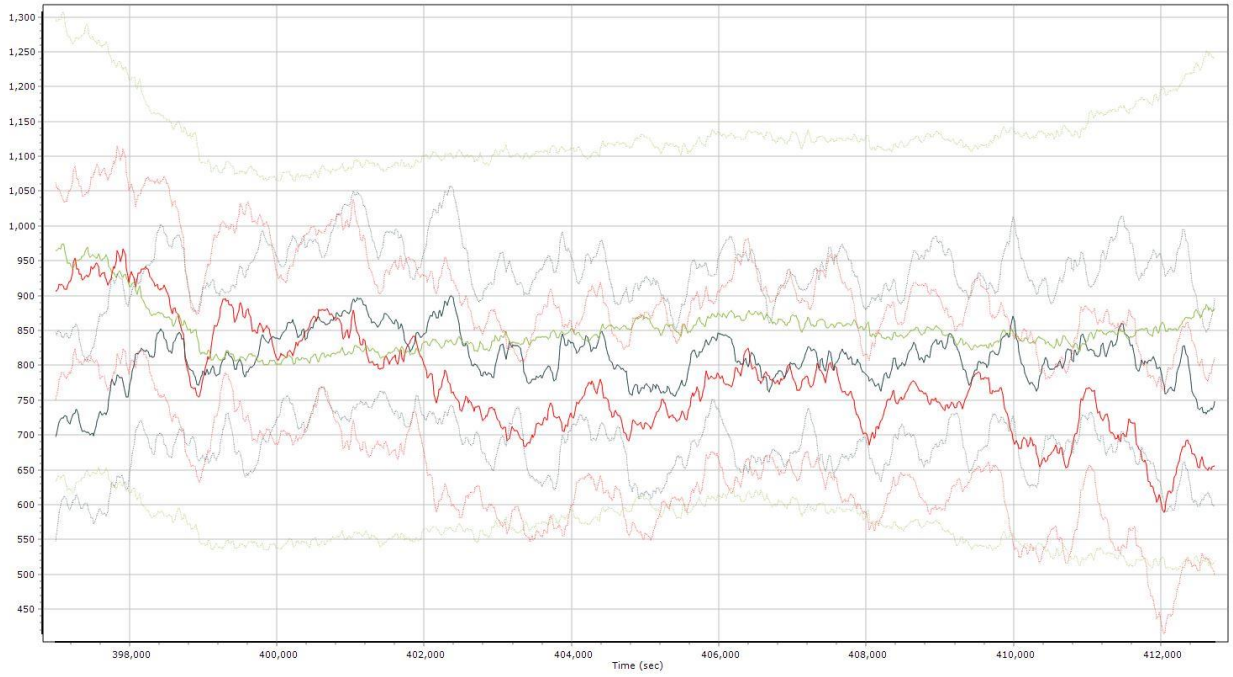


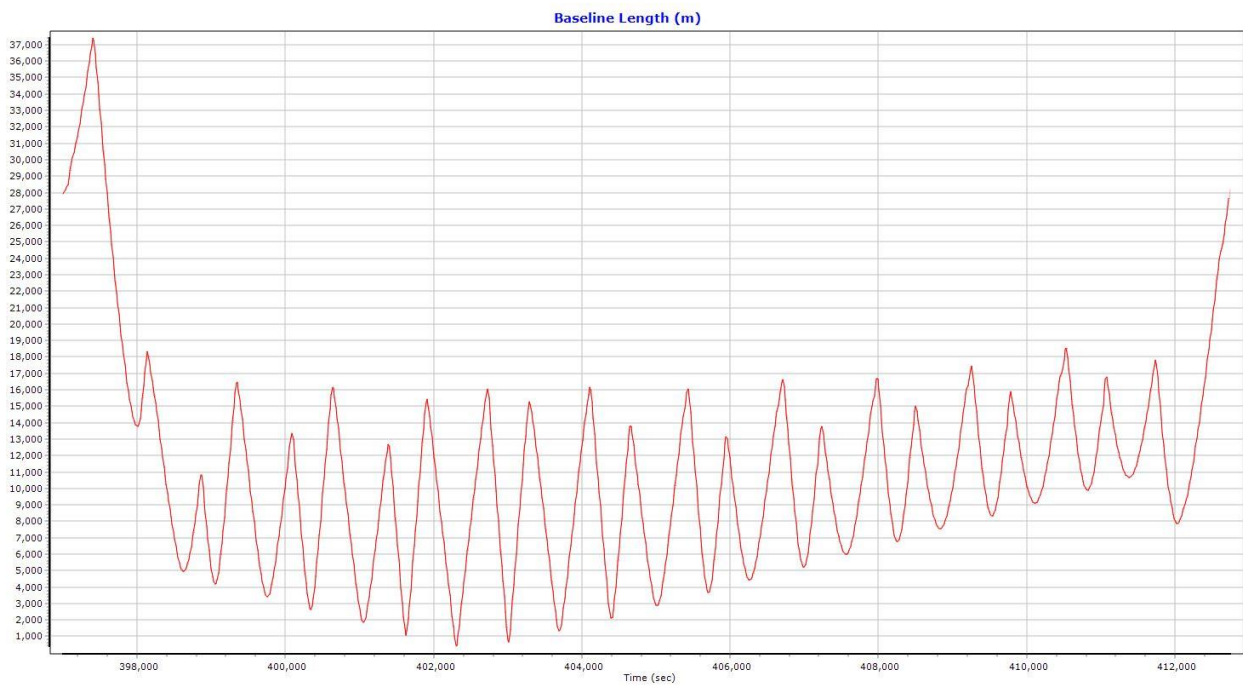
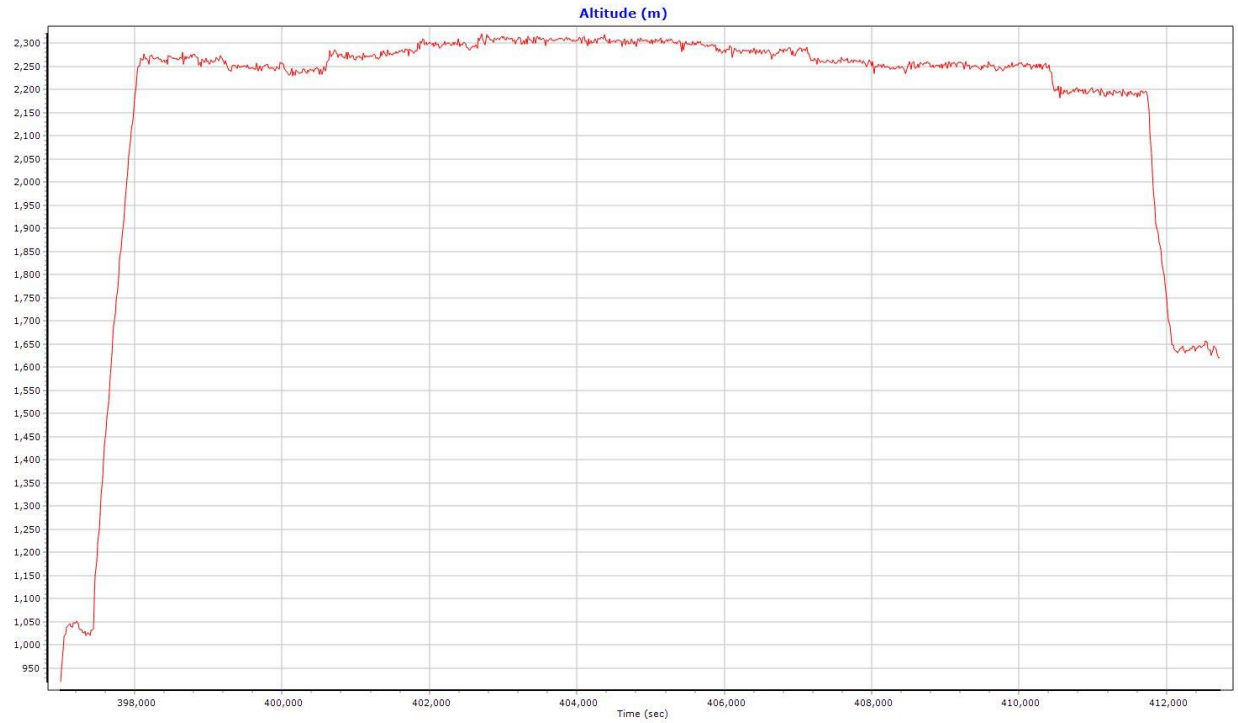






UNB18032A





Forward Reverse

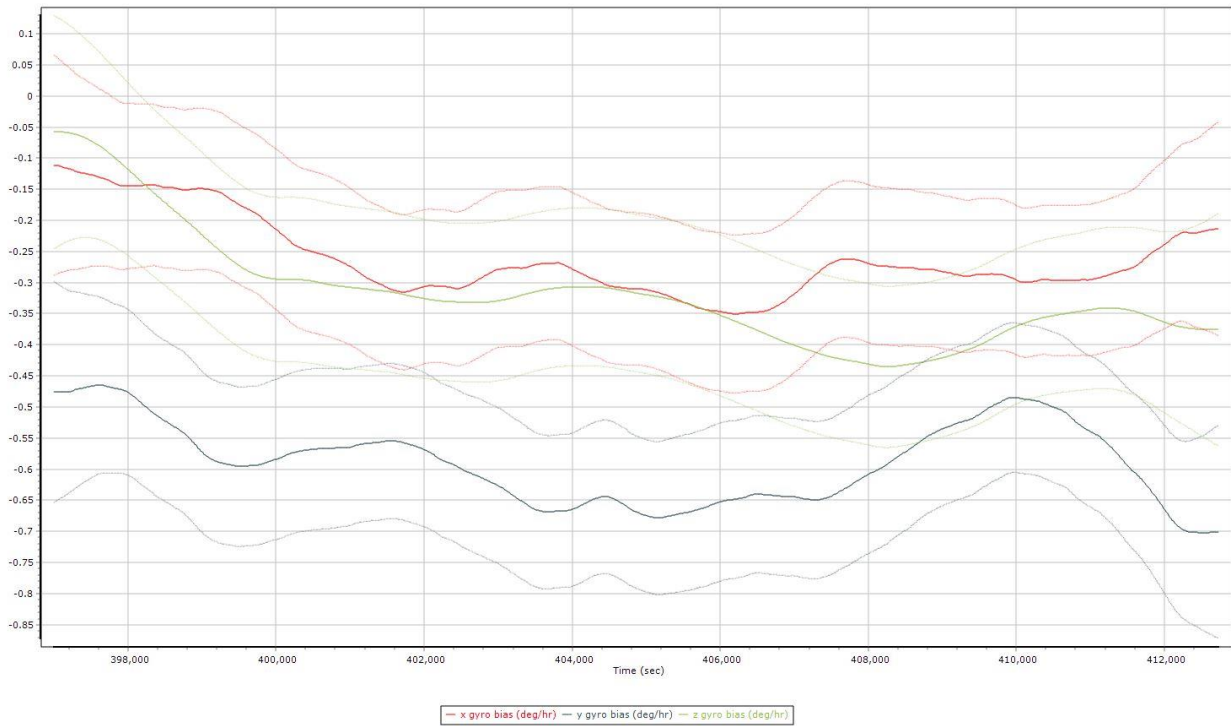
GNSS QC Statistics

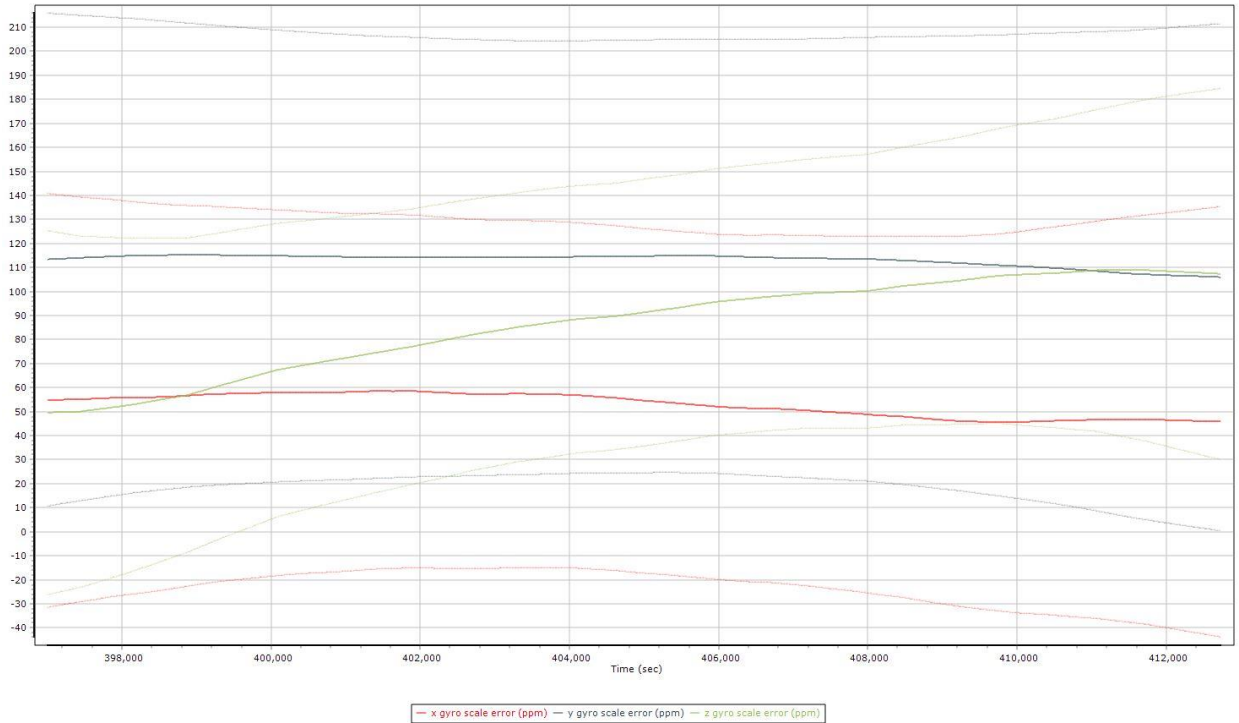


Statistics	Min	Max	Mean
Baseline Length (km)	0.29	37.43	N/A
Number of GPS SV	5	11	9
Number of GLONASS SV	0	9	7
Number of QZSS SV	0	0	0
Number of BEIDOU SV	0	0	0
Total Number of SV	8	17	15

Fixed Epoch: 17179.0 s Float Epoch: 0.0 s No Solution: 0.0 s
 Fixed Solution: 100.00% Float Solution: 0.00% No Solution: 0.00%

OK





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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

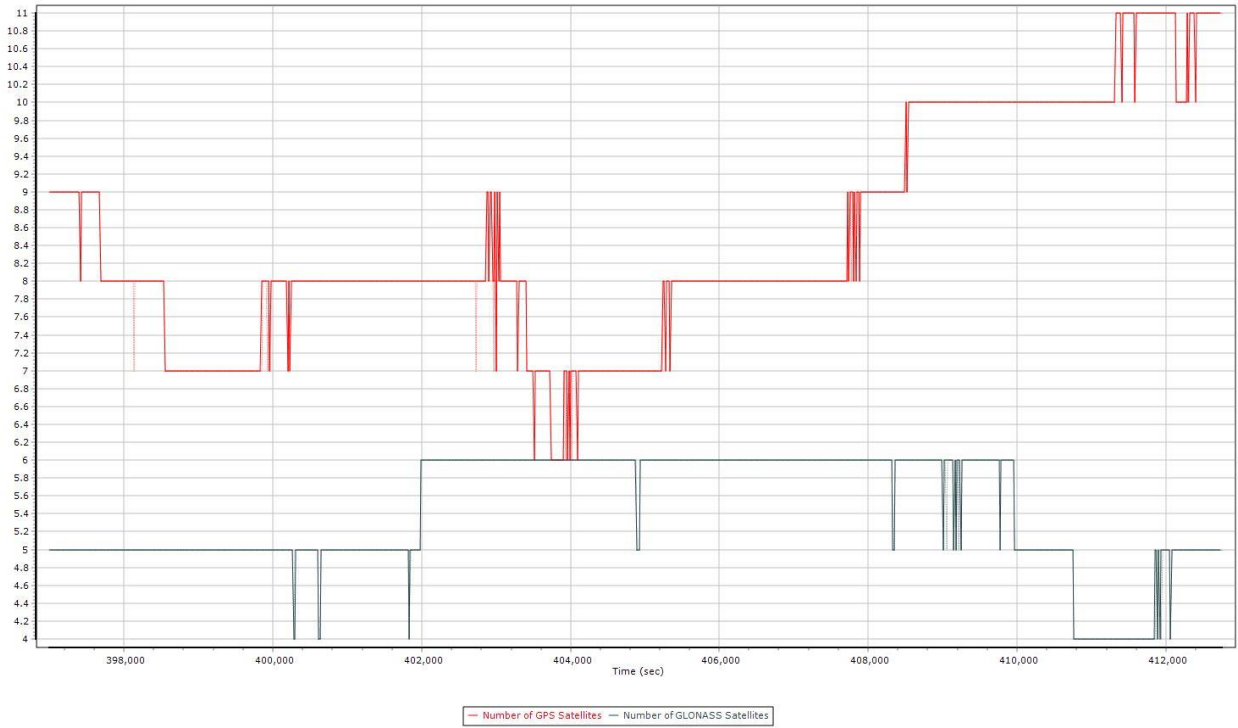
<3cm 10cm 50cm 1m 10m

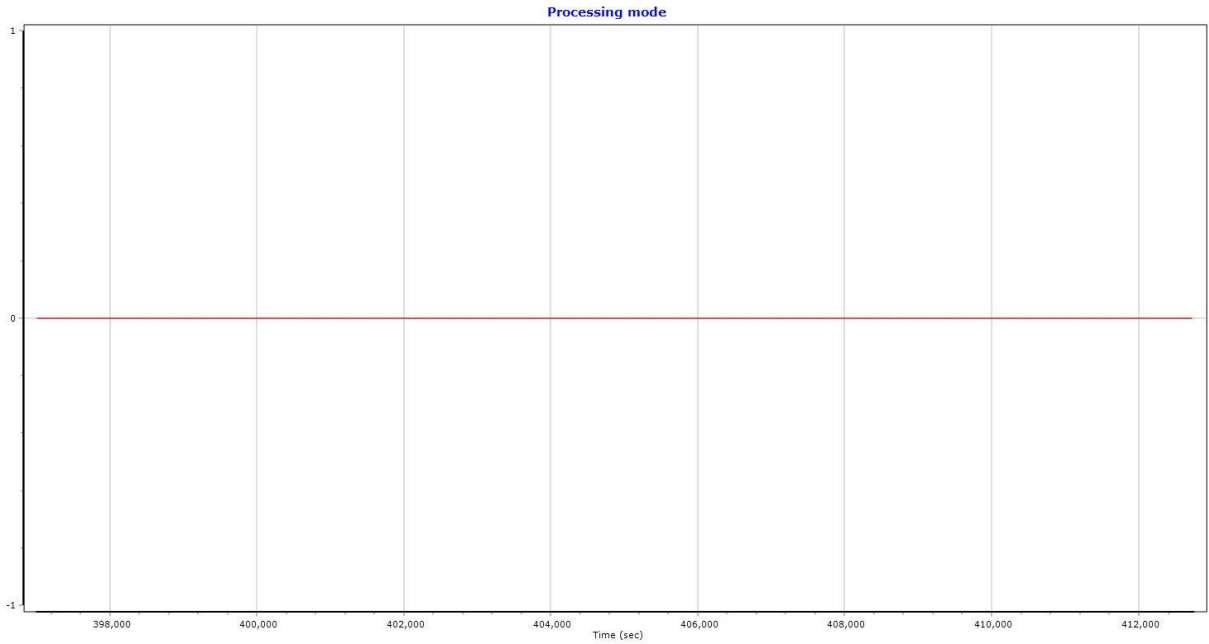
Aircraft to Reference Mounting Angles

X:

Y:

Z:



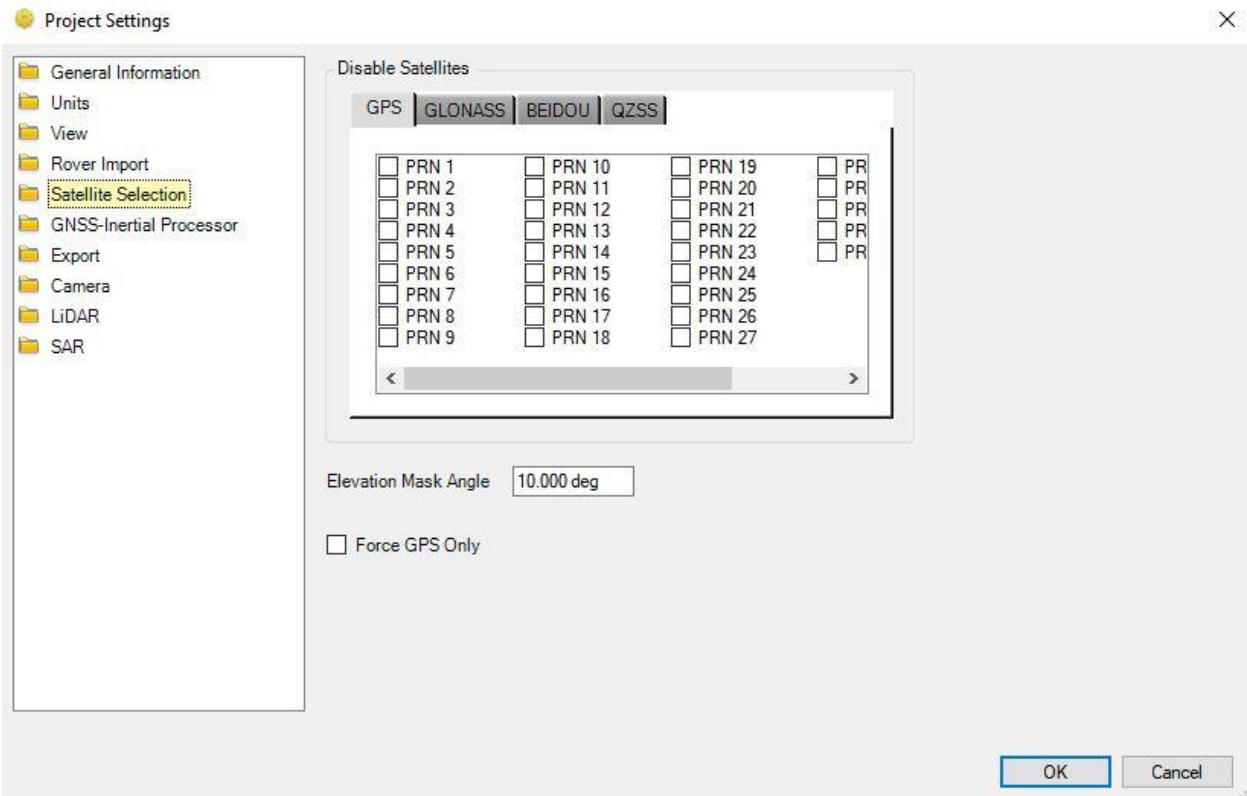
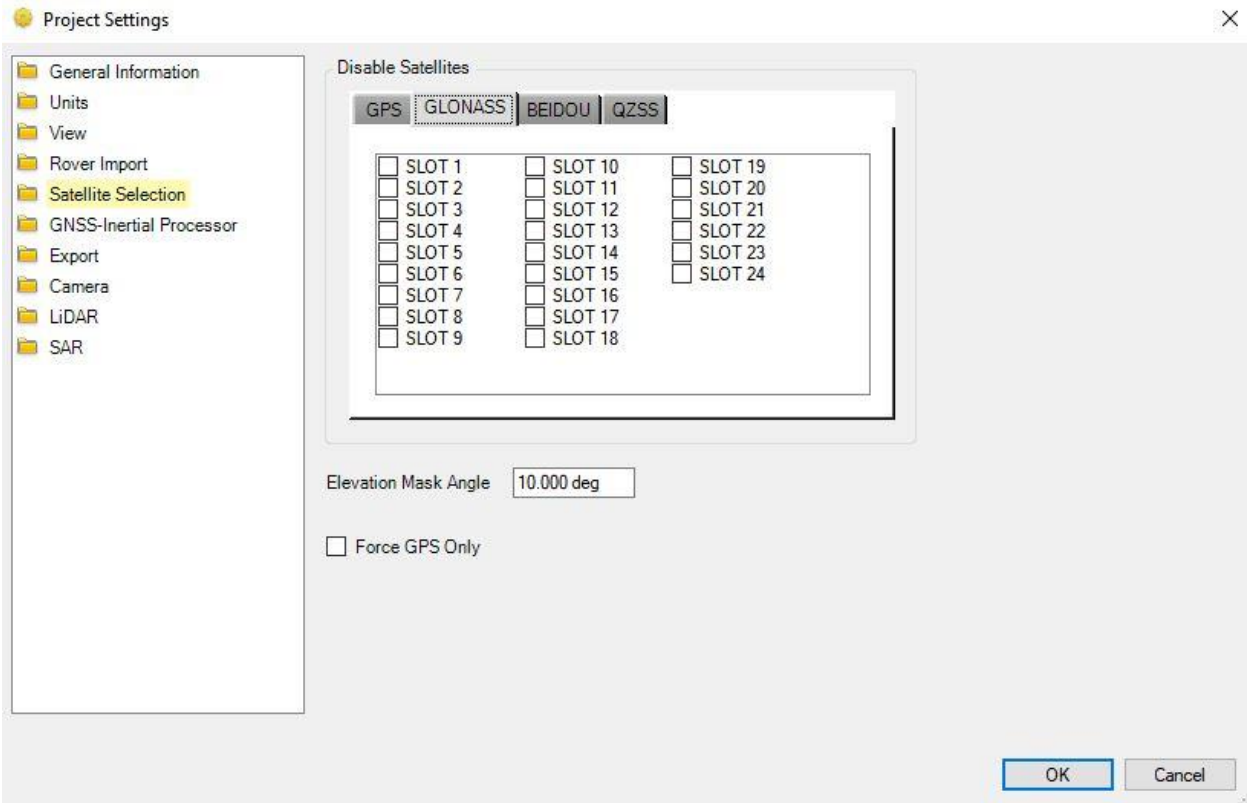


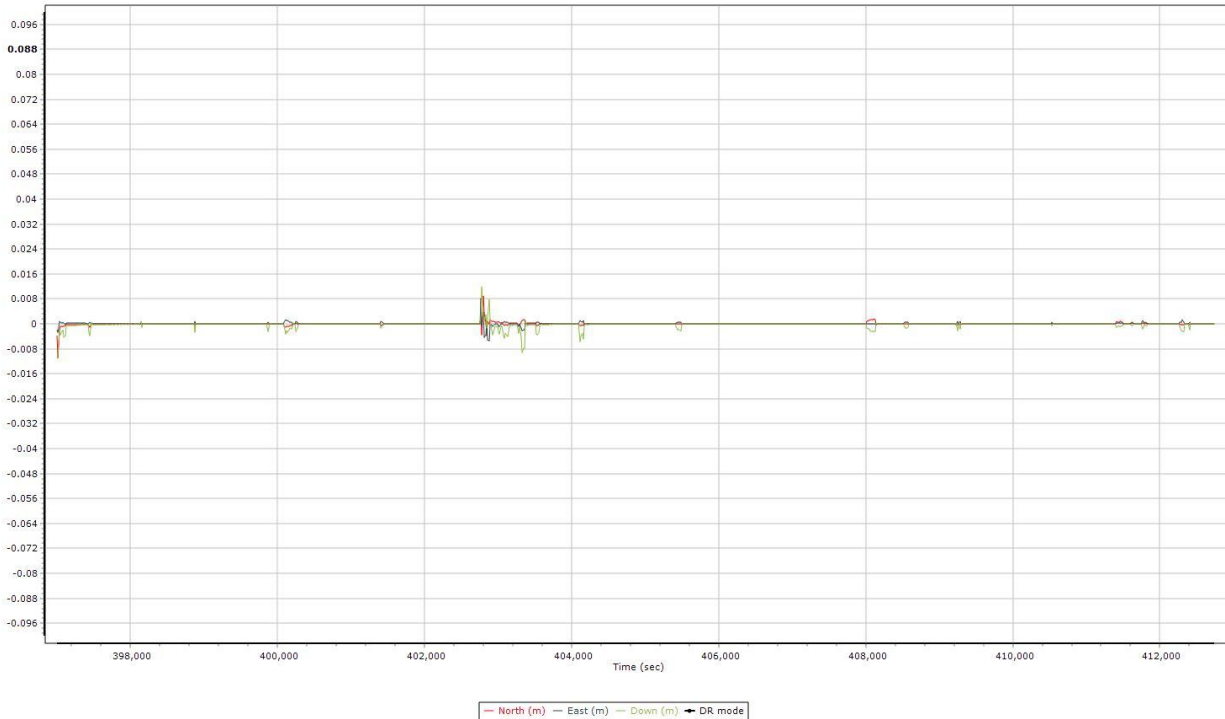
Forward Reverse

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



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





SmartBase Quality Check Results Summary



Here are the results from SmartBase Quality Check. The flashing icon below the results table suggests the next action.

Station	Status	Horizontal	Vertical	Total	Time Span	Output Coords
TXAL	Control	0.000 m	0.000 m	0.000 m	23.90 h	Control
TXAB	OK	0.014 m	0.010 m	0.018 m	23.90 h	Original
TXC0	OK	0.008 m	0.013 m	0.015 m	23.90 h	Original
SMSW	OK	0.010 m	0.003 m	0.010 m	23.90 h	Original
TXRL	OK	0.012 m	0.017 m	0.021 m	23.90 h	Original
TXC3	OK	0.017 m	0.017 m	0.024 m	23.90 h	Original
TXBI	OK	0.017 m	0.000 m	0.017 m	23.90 h	Original

Choose any of the available actions or click 'Continue' to proceed with the suggested action. The 'Output Coords' column contains the recommended coordinate setting for the next action.

Run the SmartBase Quality Check processor with the next best control candidate.



Re-run the SmartBase Quality Check processor.

Continue



Run the Applanix SmartBase processor.

Close

Project Settings

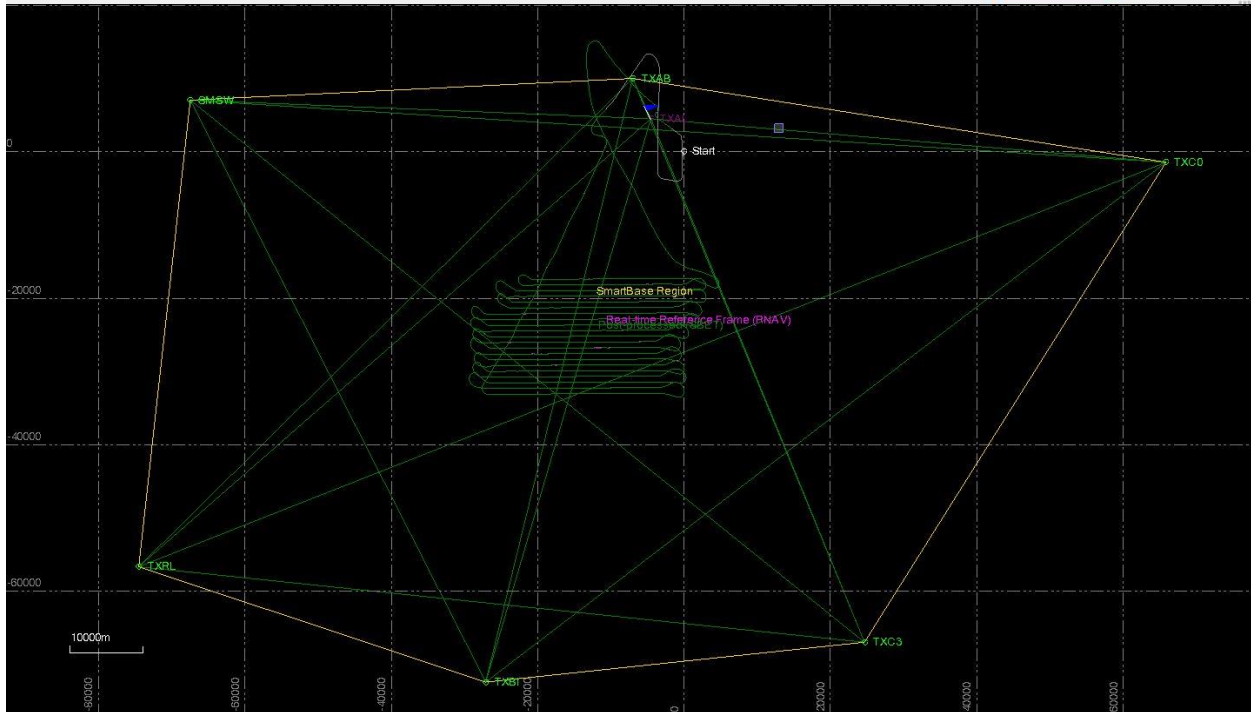
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing**
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

Timing

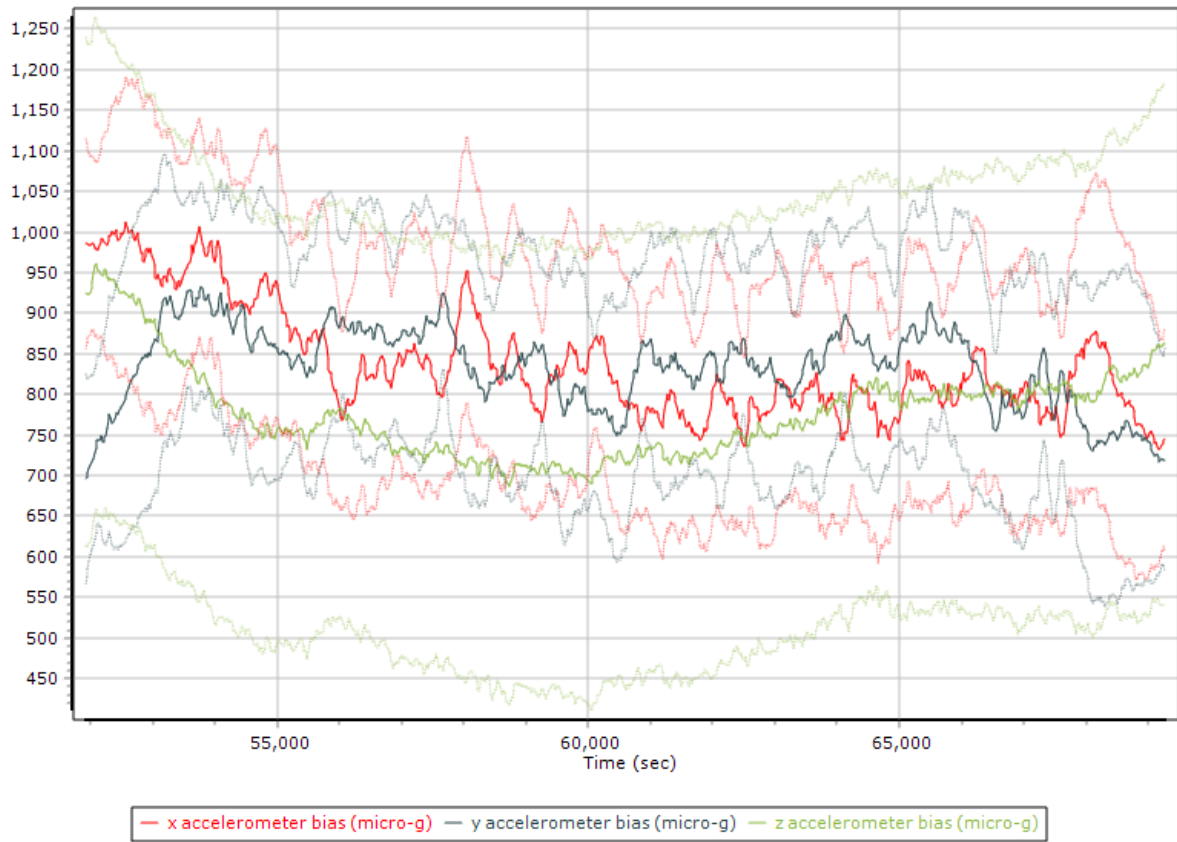
Start: 397000.000
End: 412750.000
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

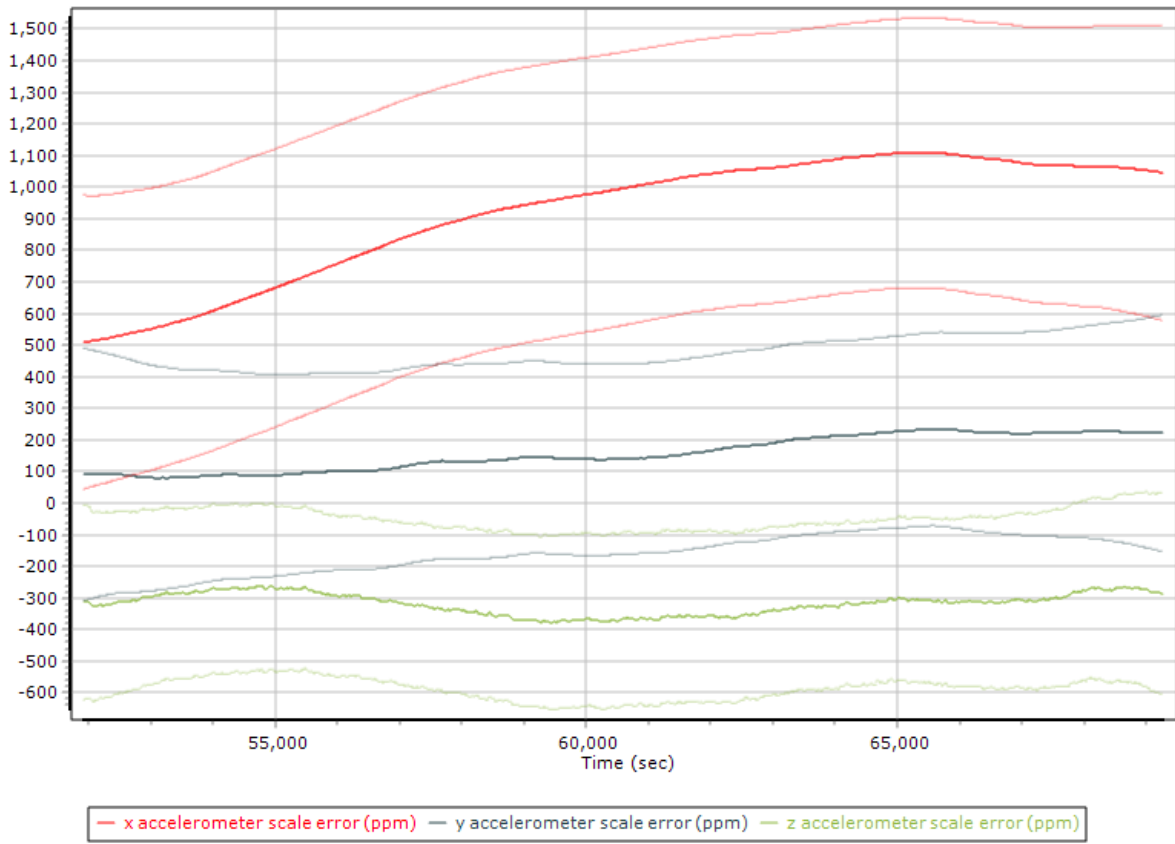
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

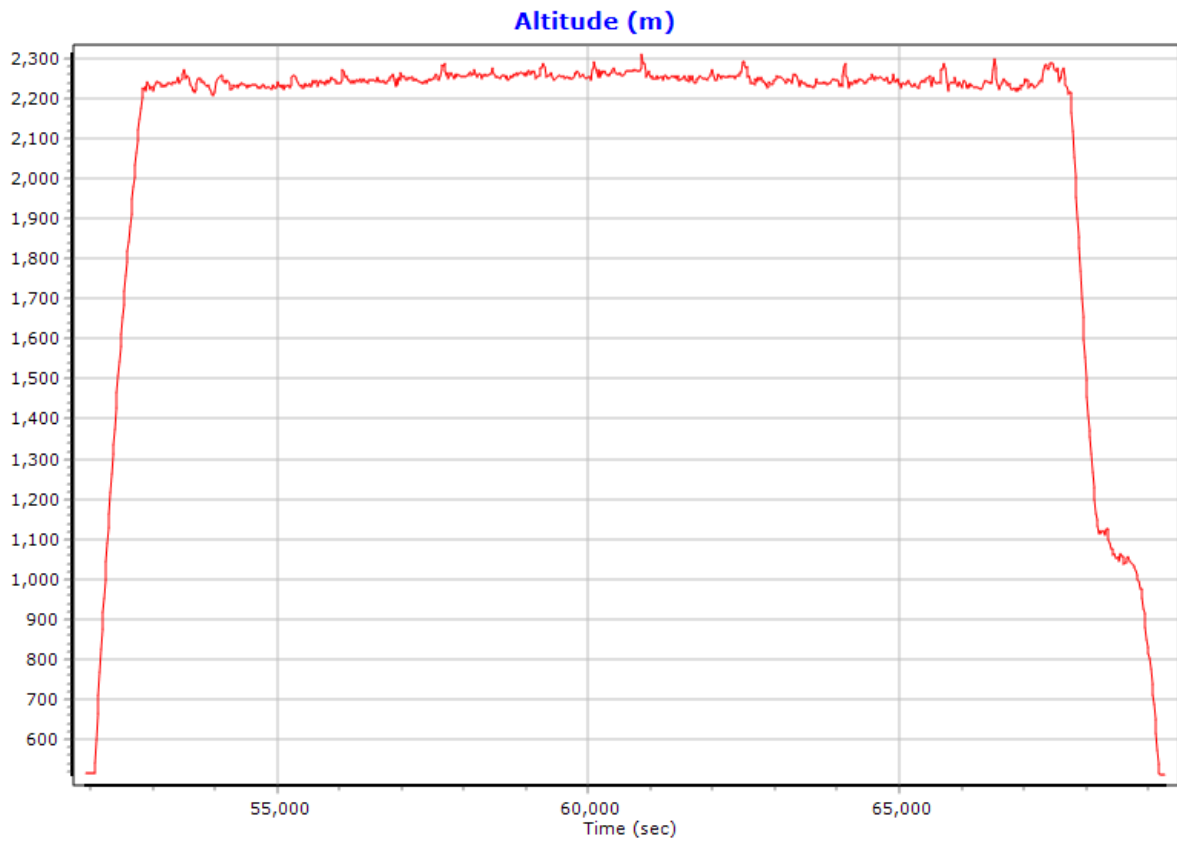
OK Cancel

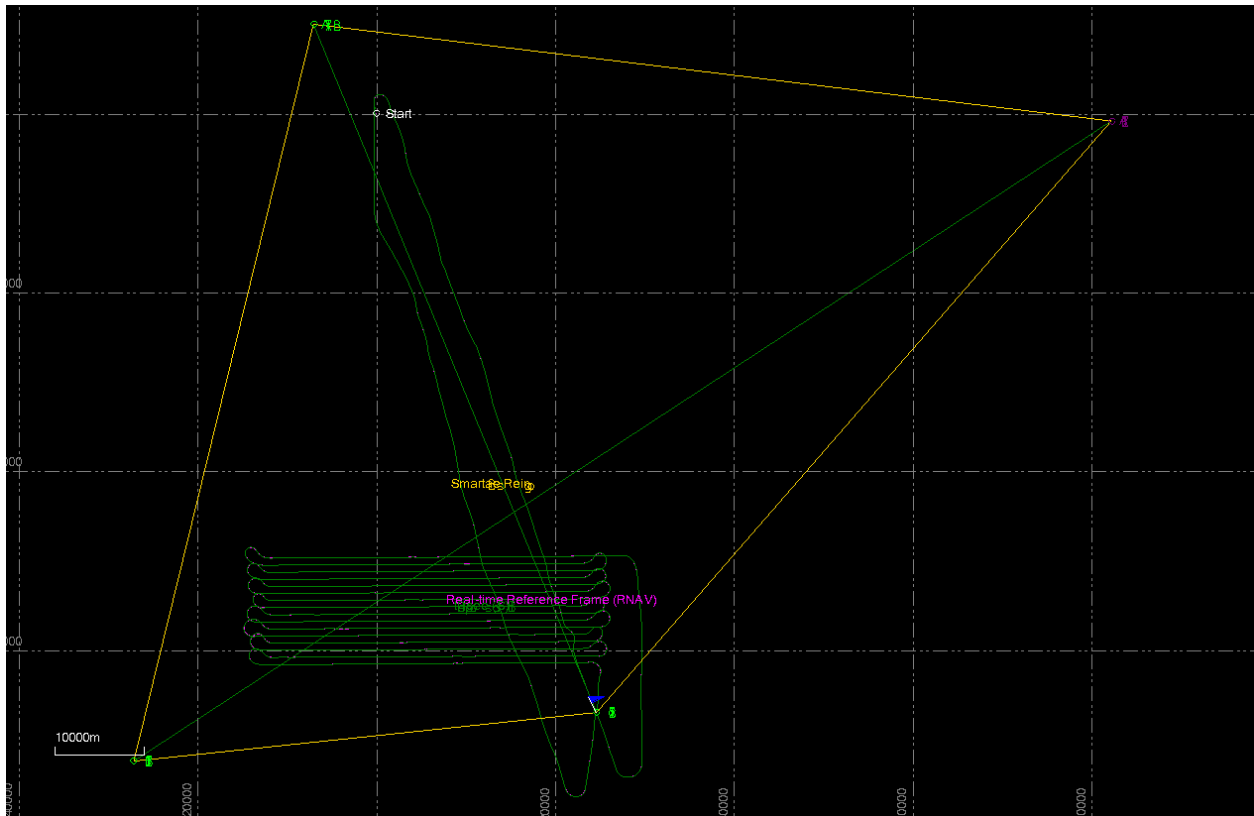
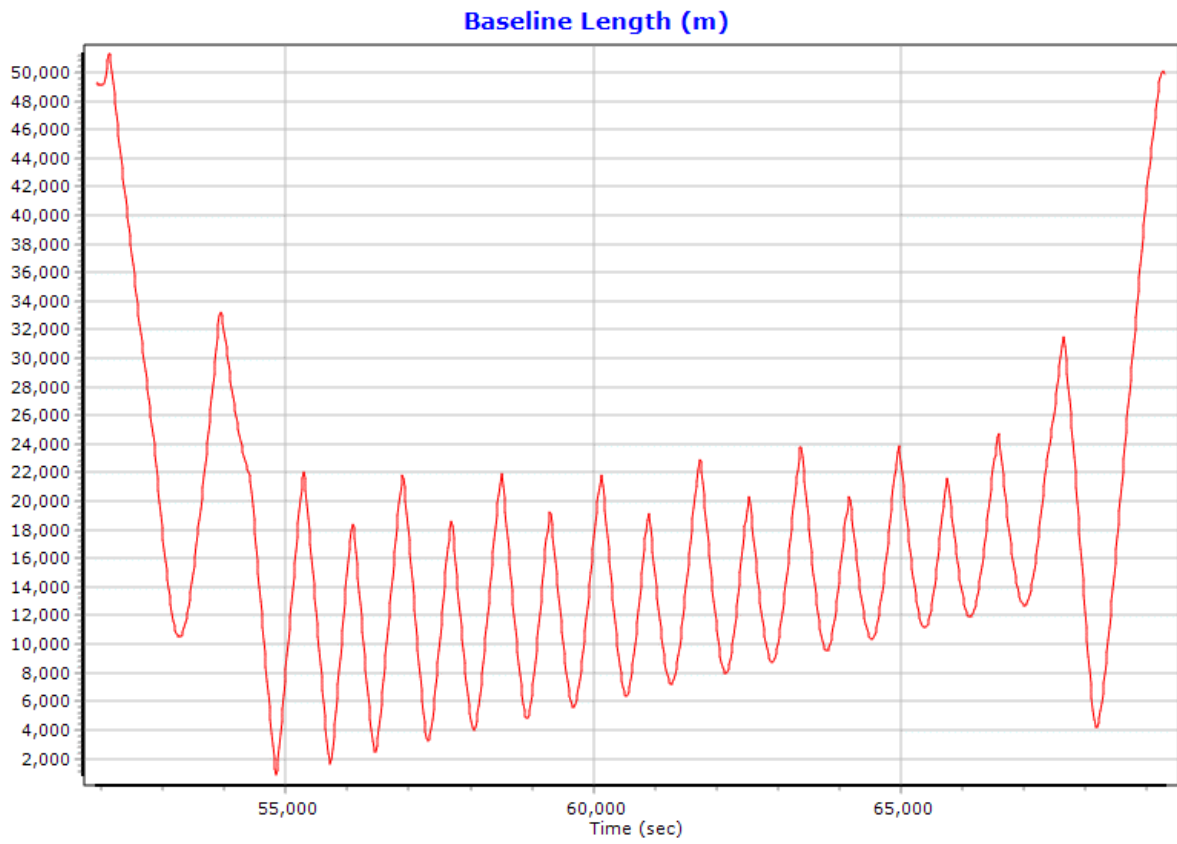


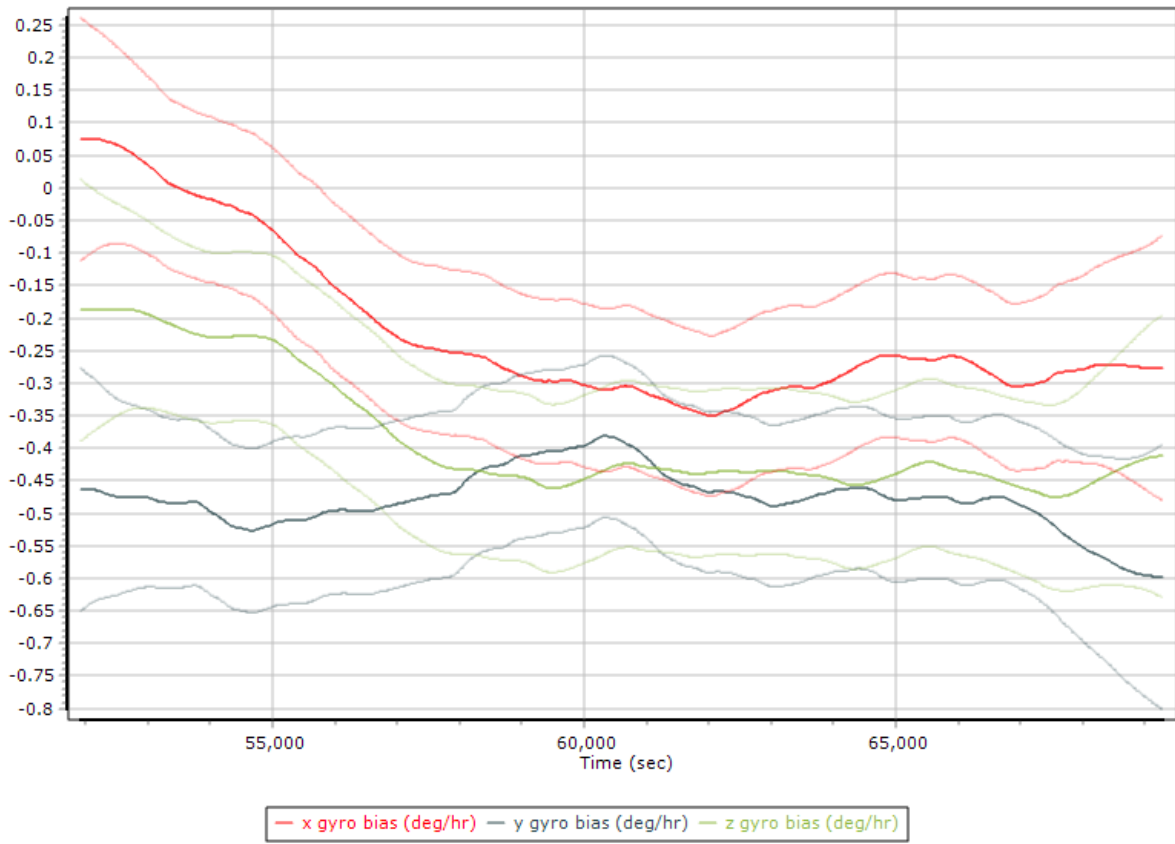
UNB18035A

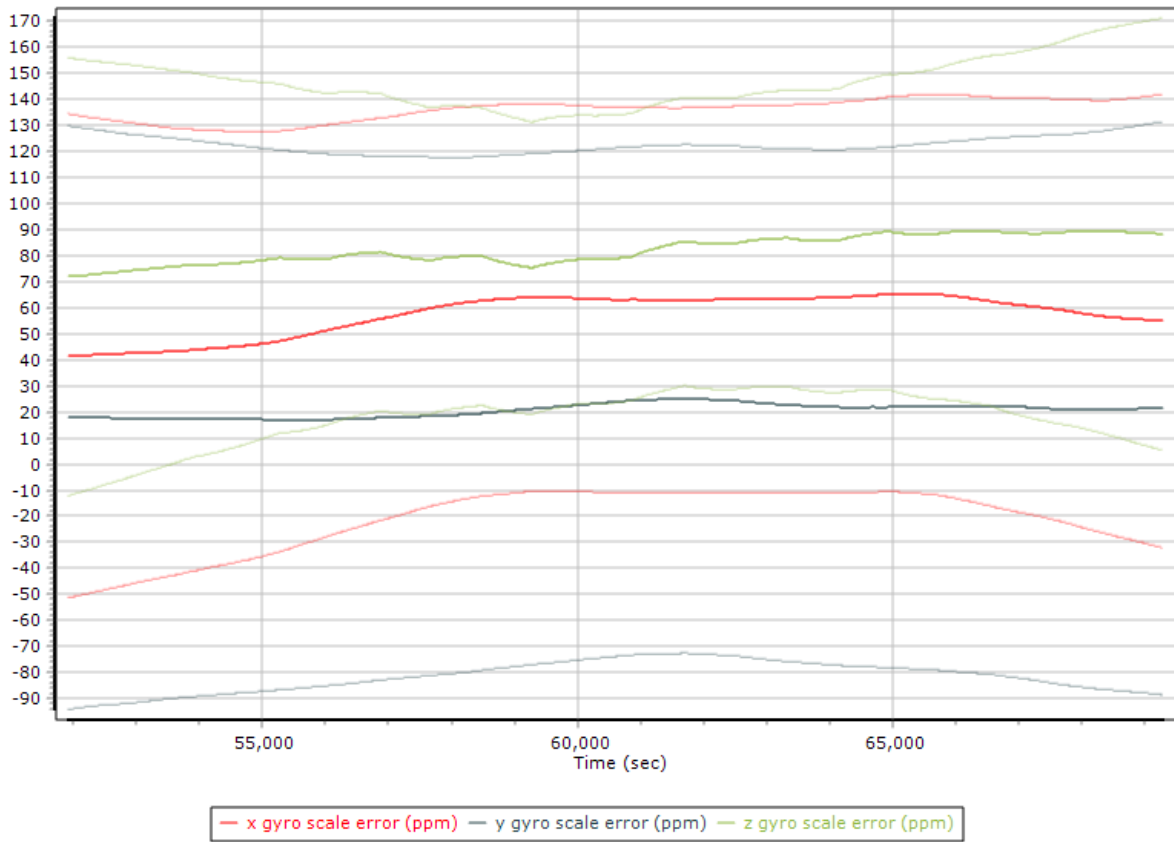












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

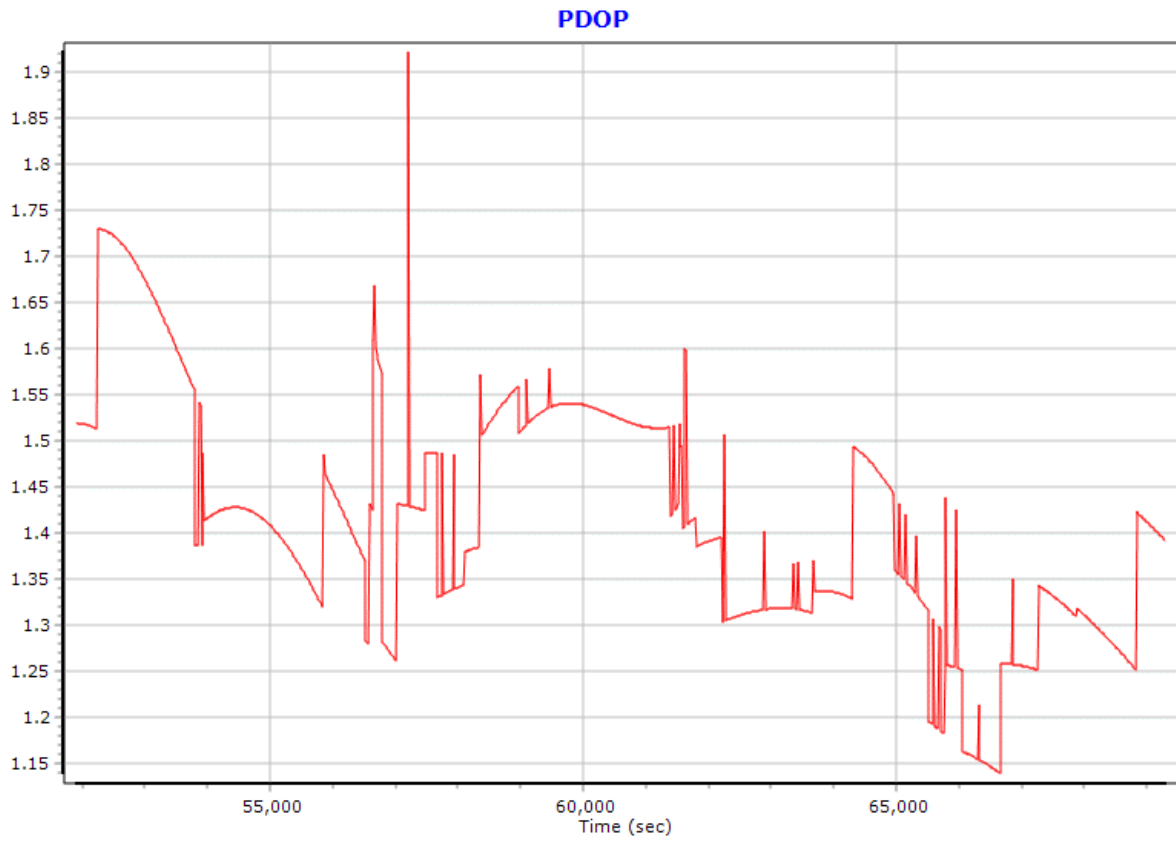
<3cm 10cm 50cm 1m 10m

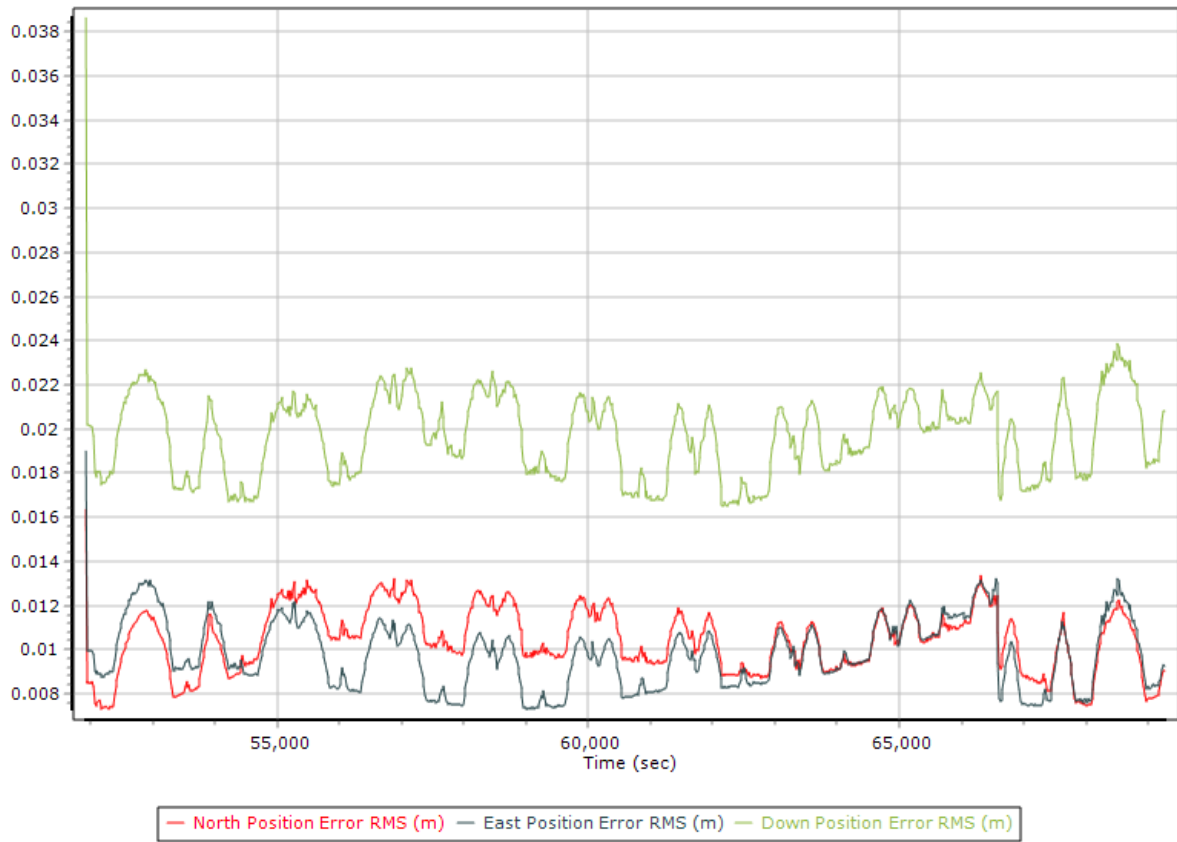
Aircraft to Reference Mounting Angles

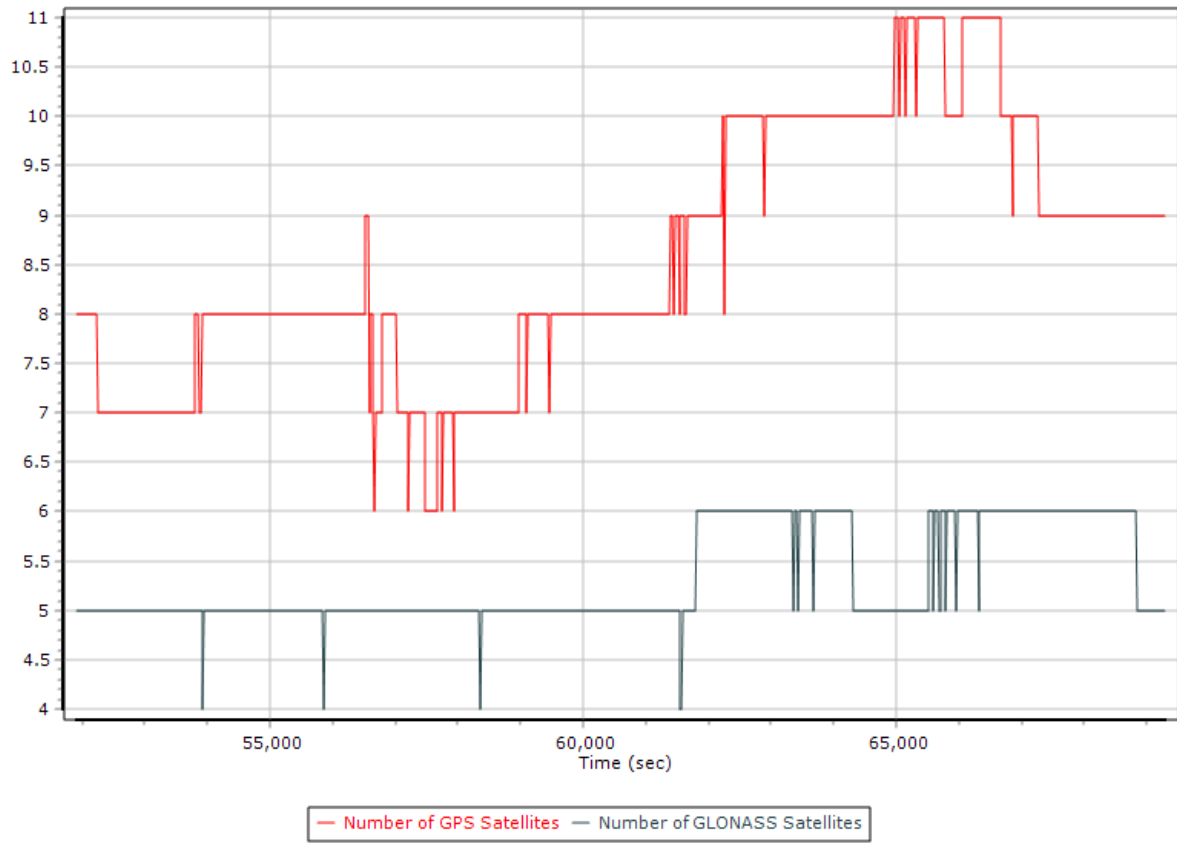
X:

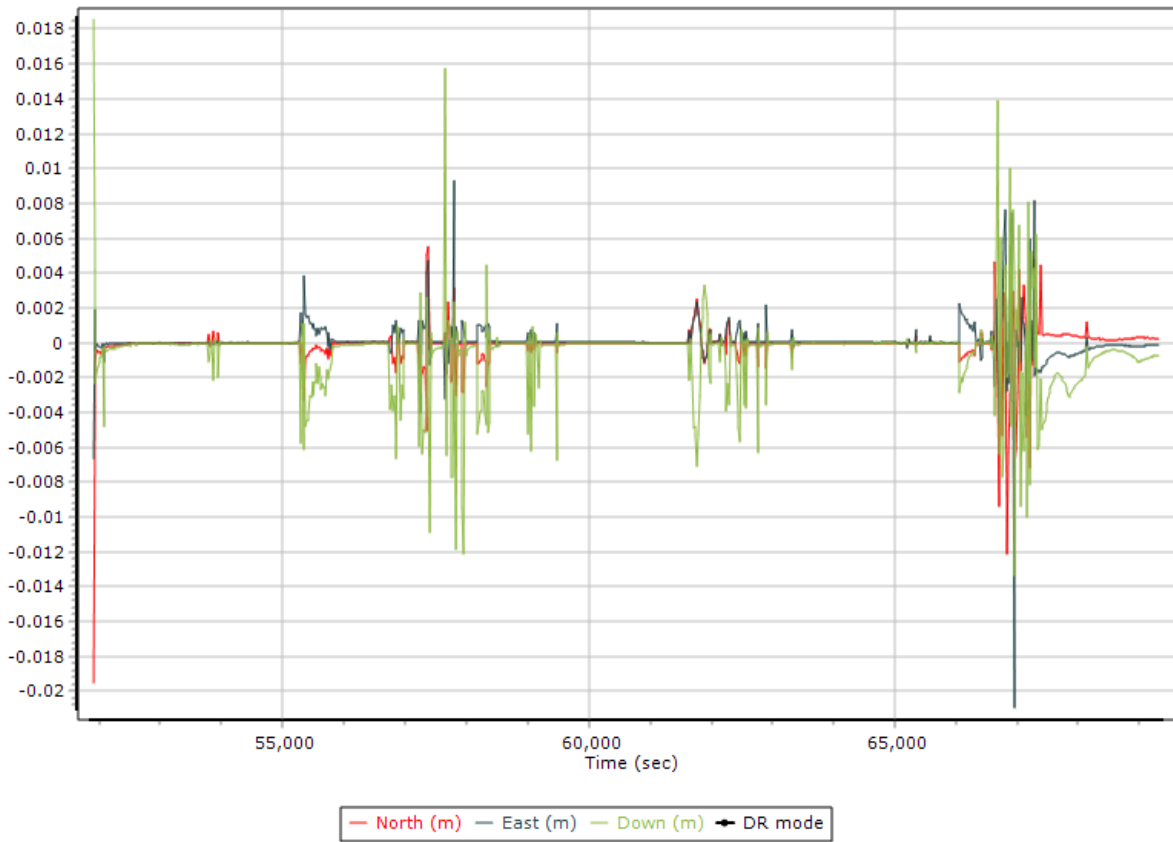
Y:

Z:









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: 51107.000
End: 69299.000

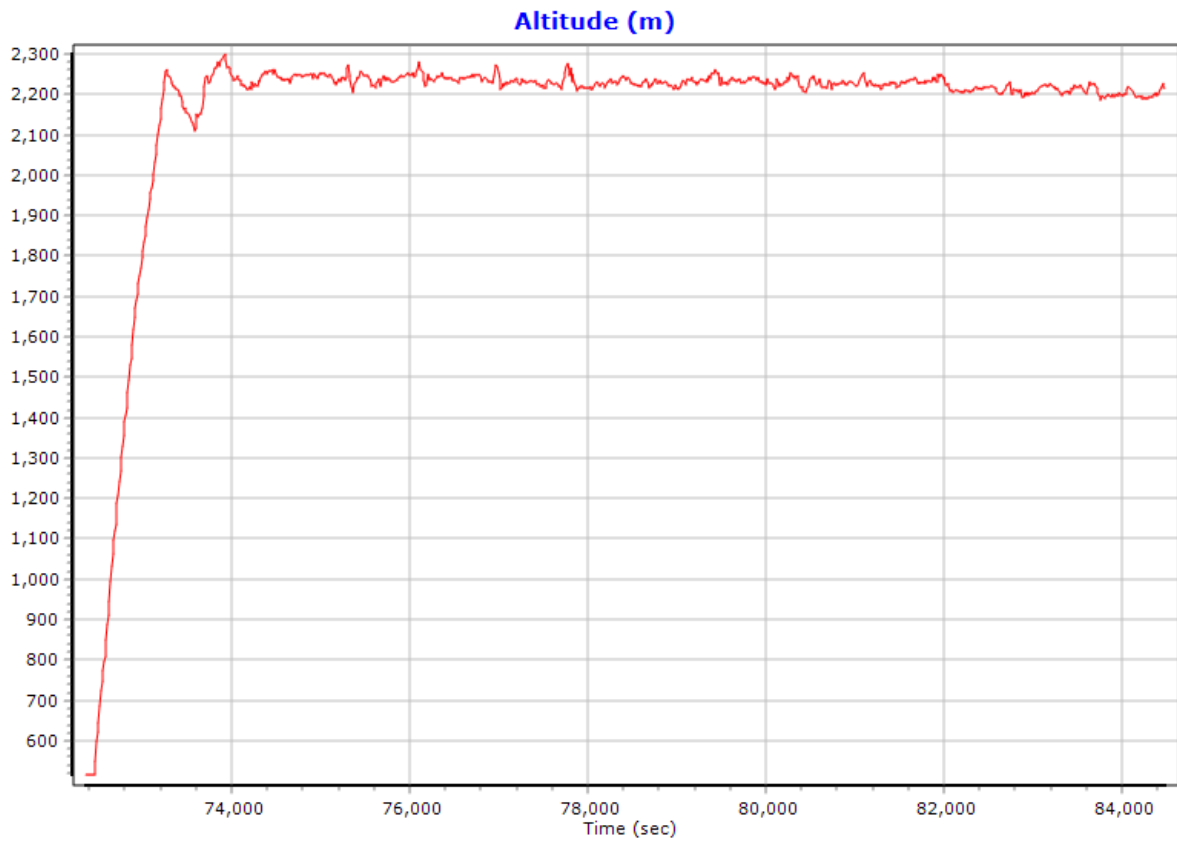
Entire time interval
 Seconds of start week

UTC Offset: 18.000

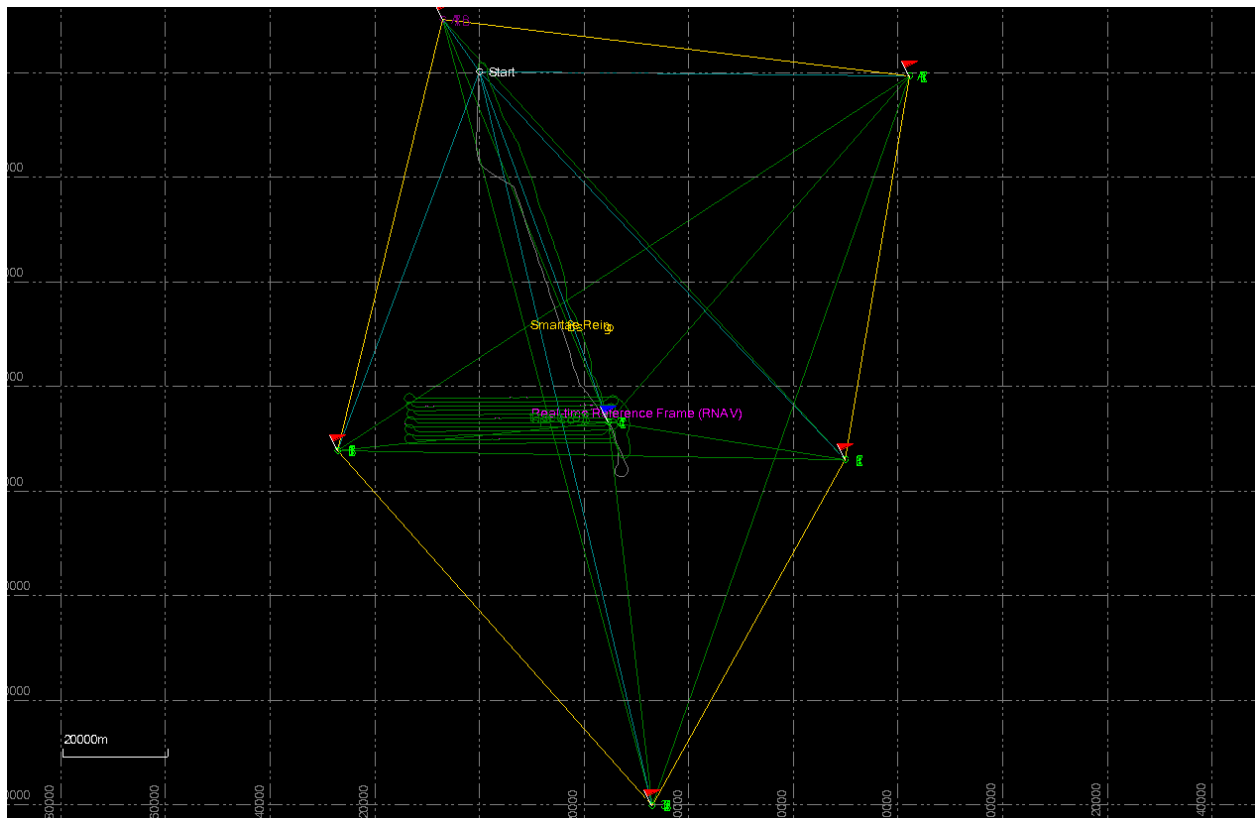
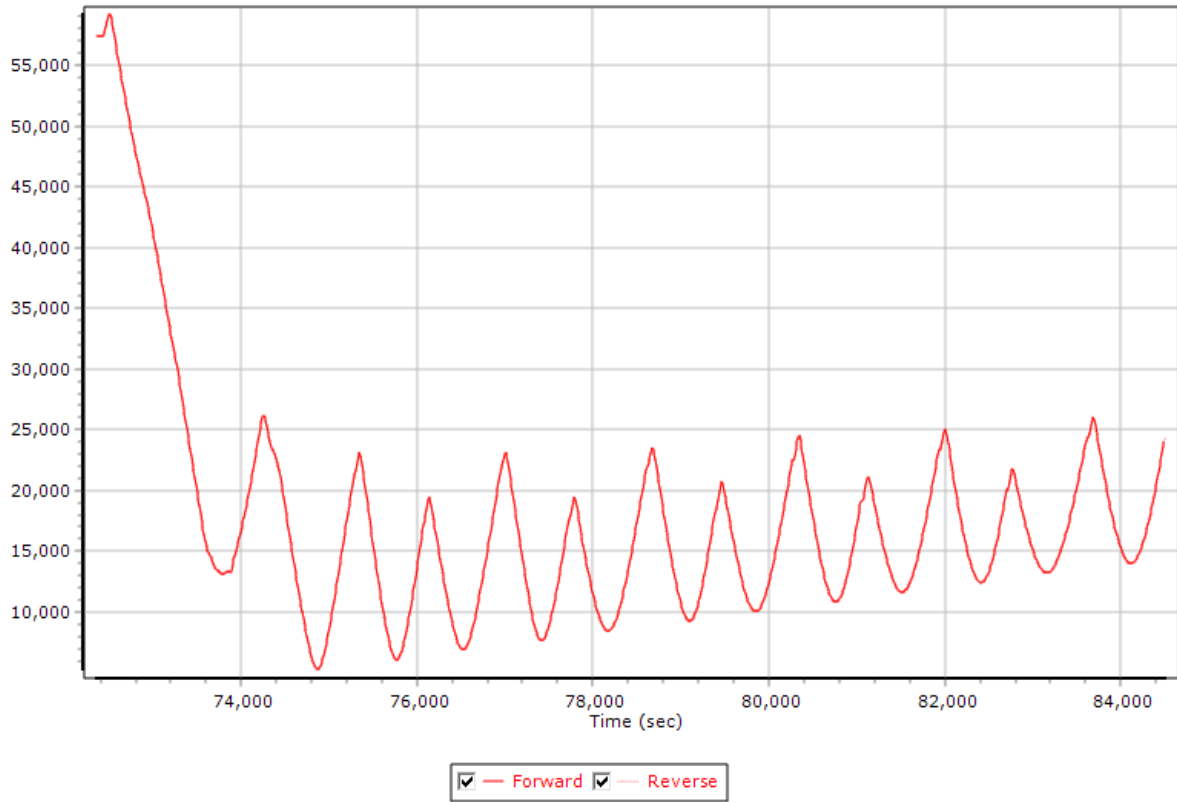
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

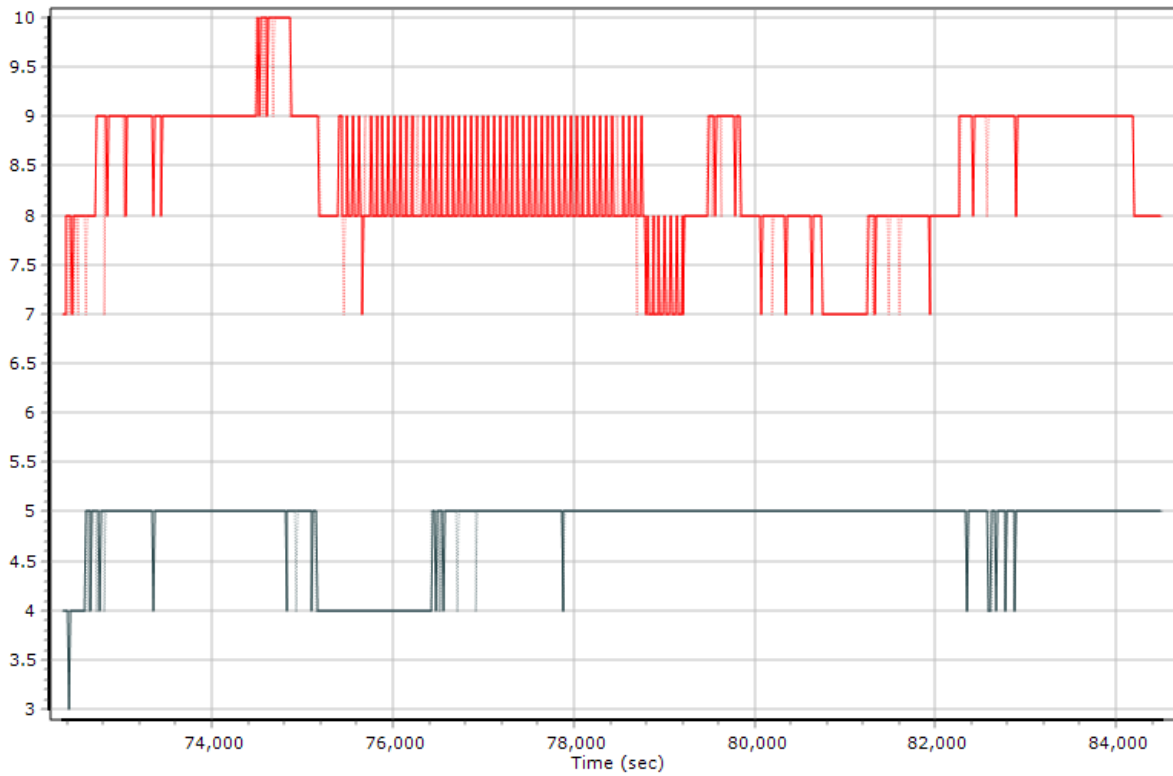
OK Cancel

UNB18035B



Baseline Length (m)





— Number of GPS Satellites — Number of GLONASS Satellites

Project Settings ✕

- General Information
- Units
- View
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 - Timing
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 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation

<3cm 10cm 50cm 1m 10m

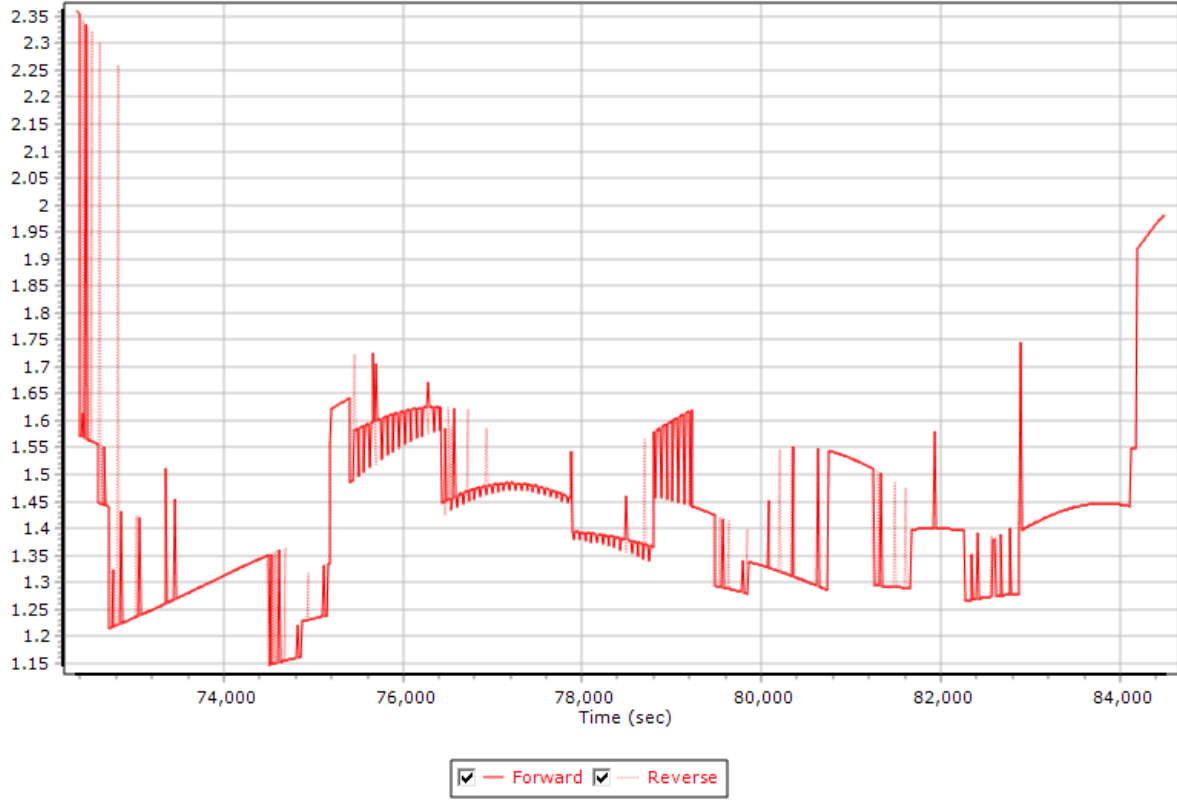
Aircraft to Reference Mounting Angles

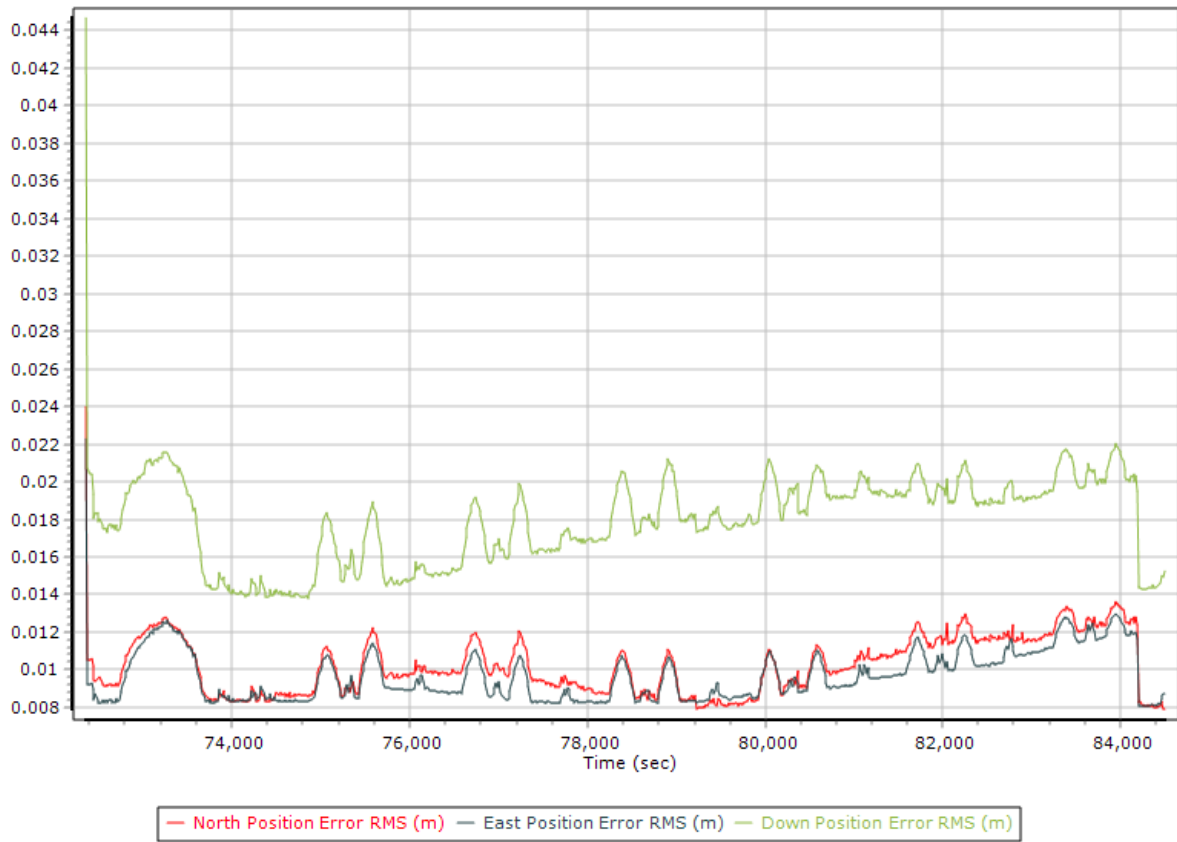
X:

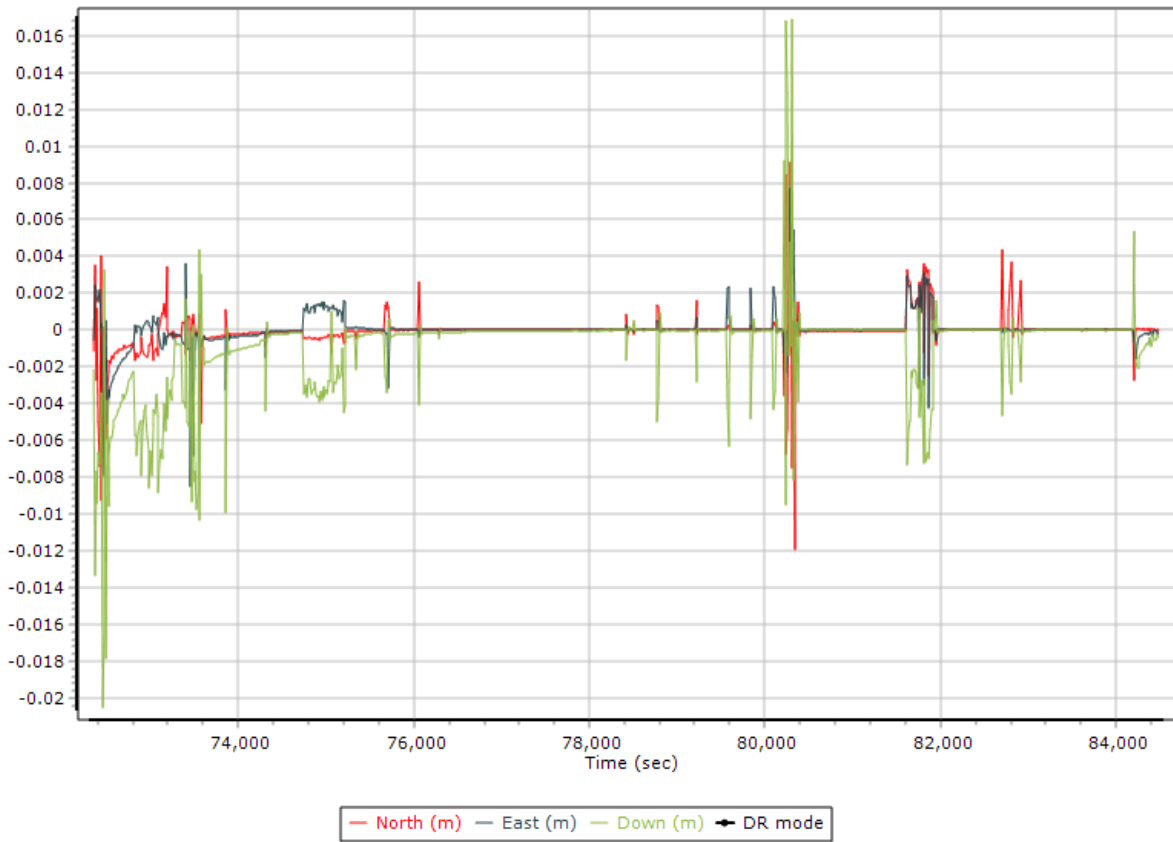
Y:

Z:

PDOP







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

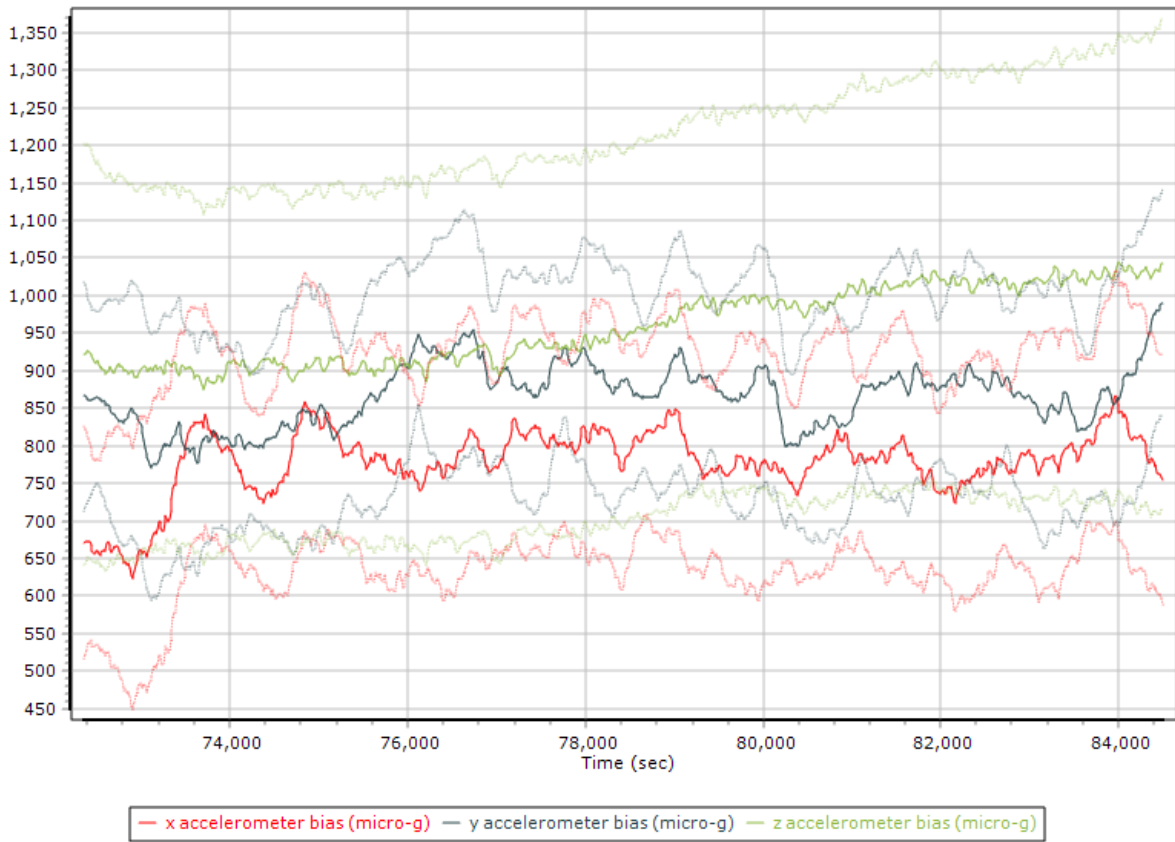
Start: 72214.065
End: 84507.522

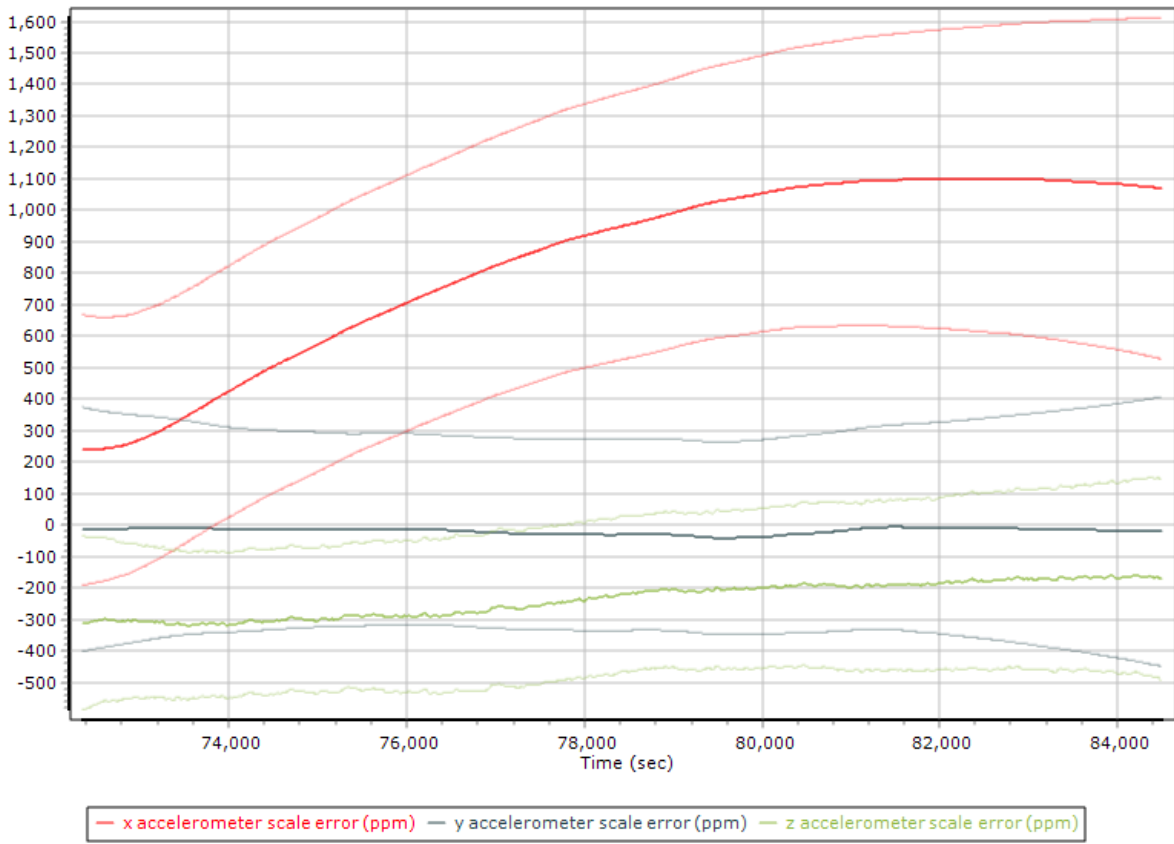
Entire time interval
 Seconds of start week

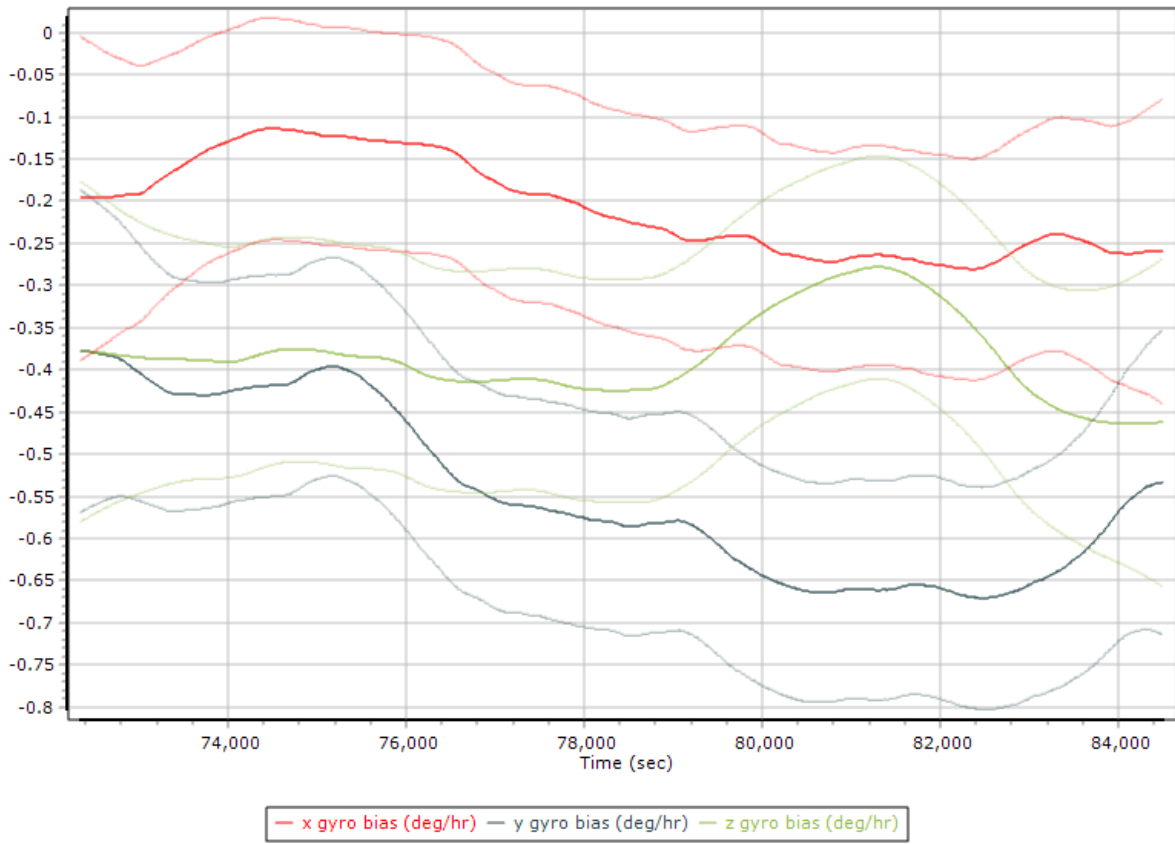
UTC Offset: 18.000

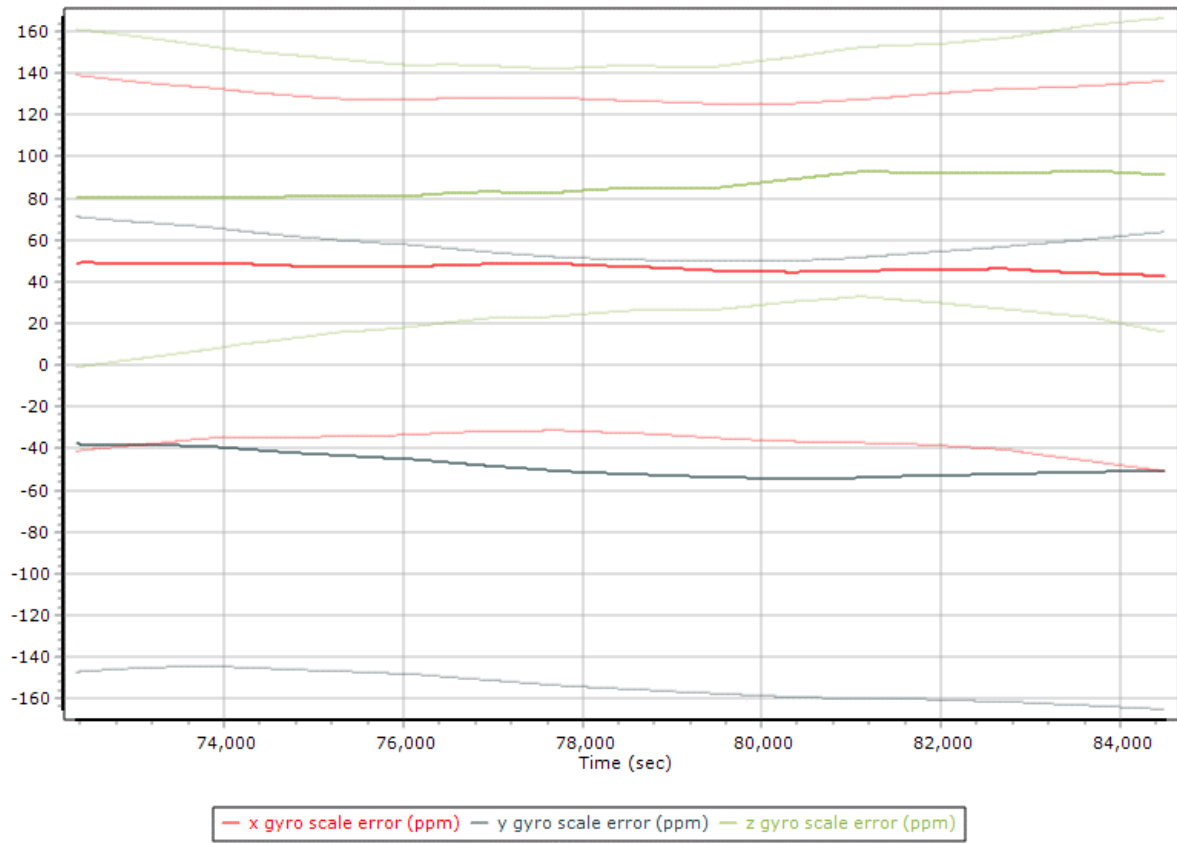
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel

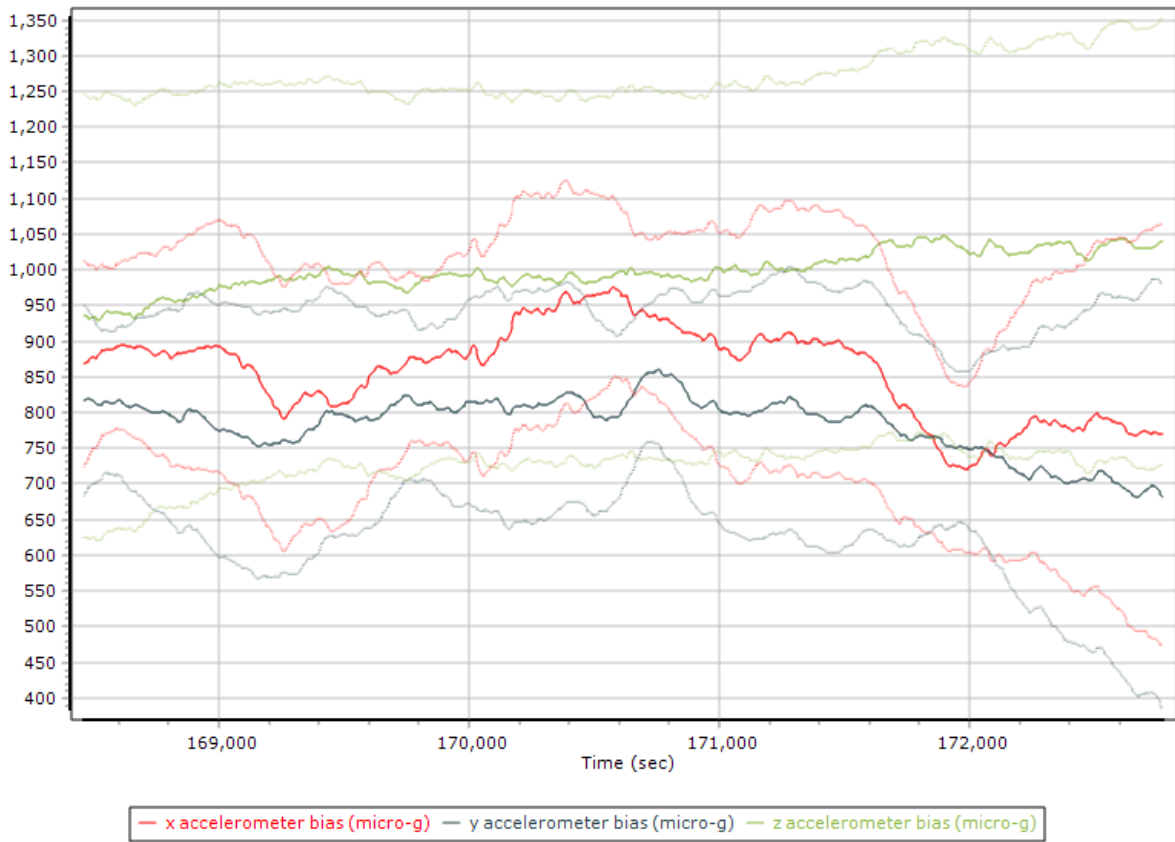


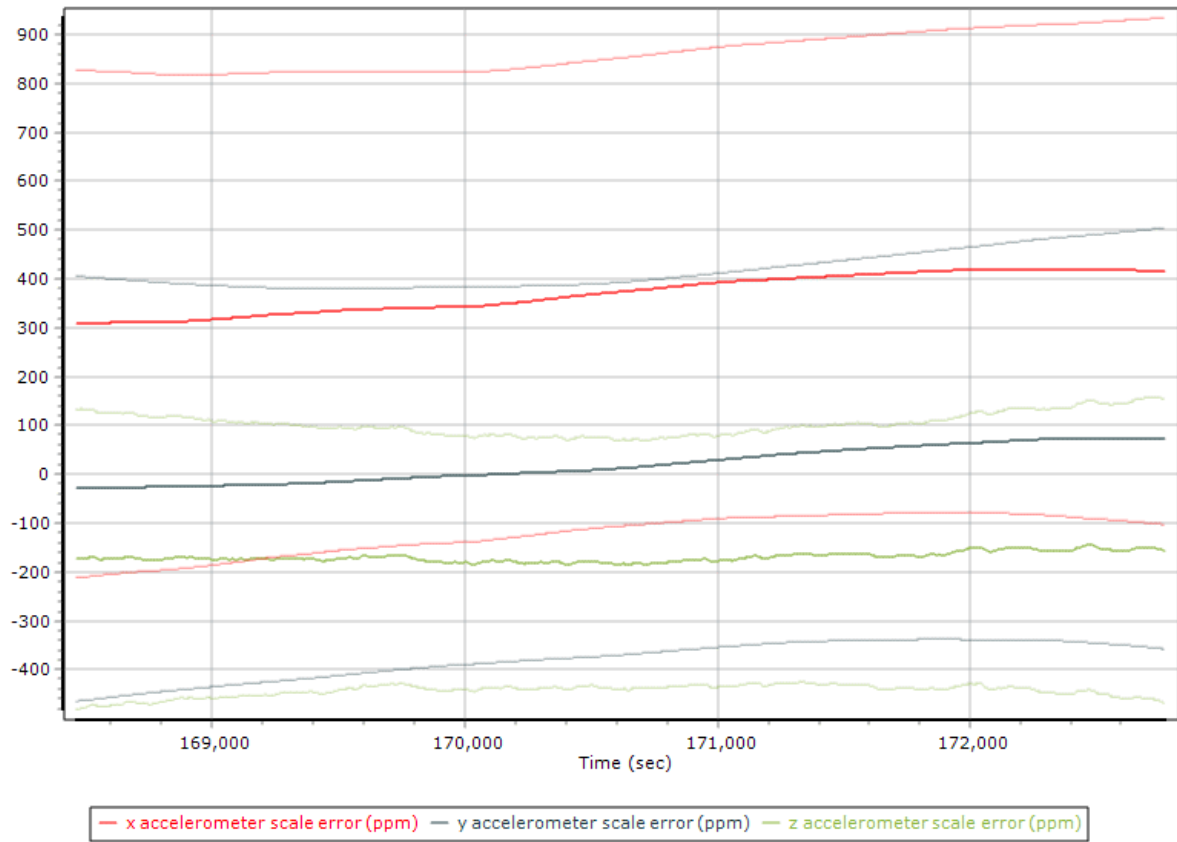


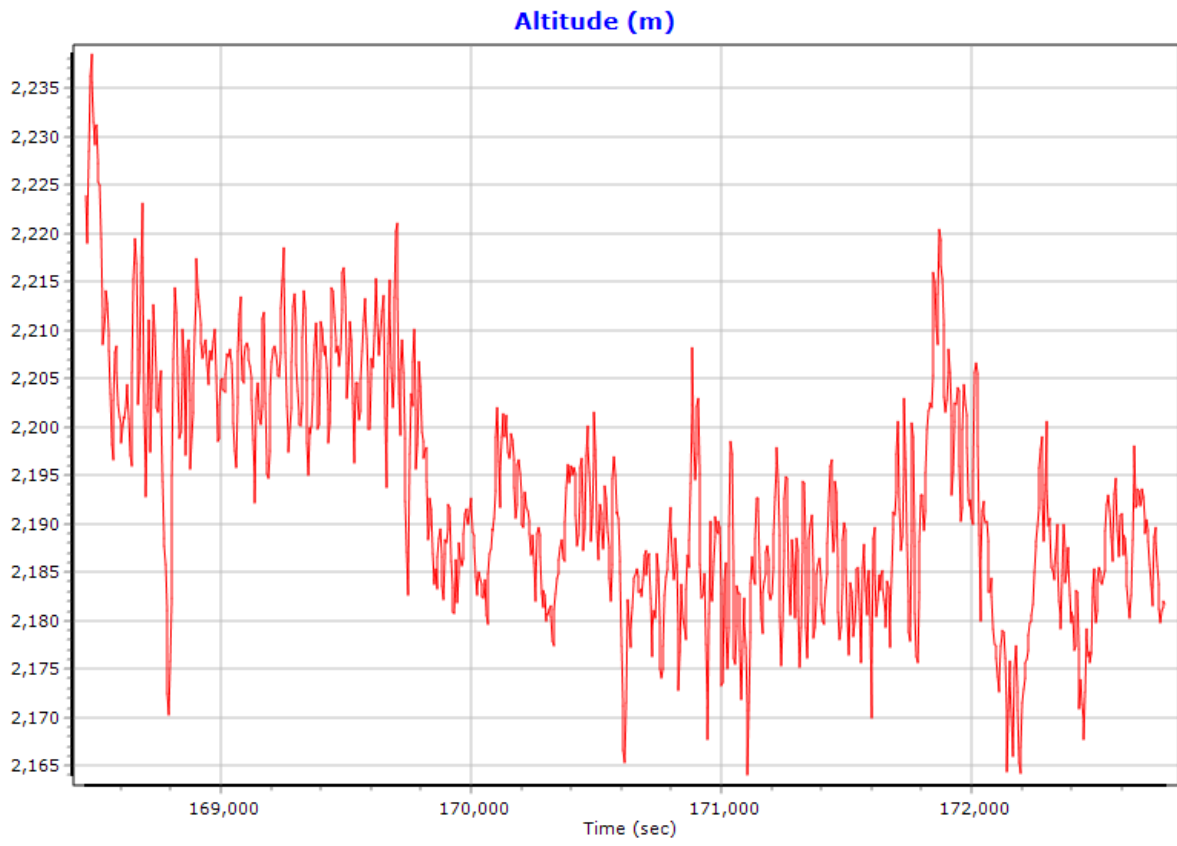


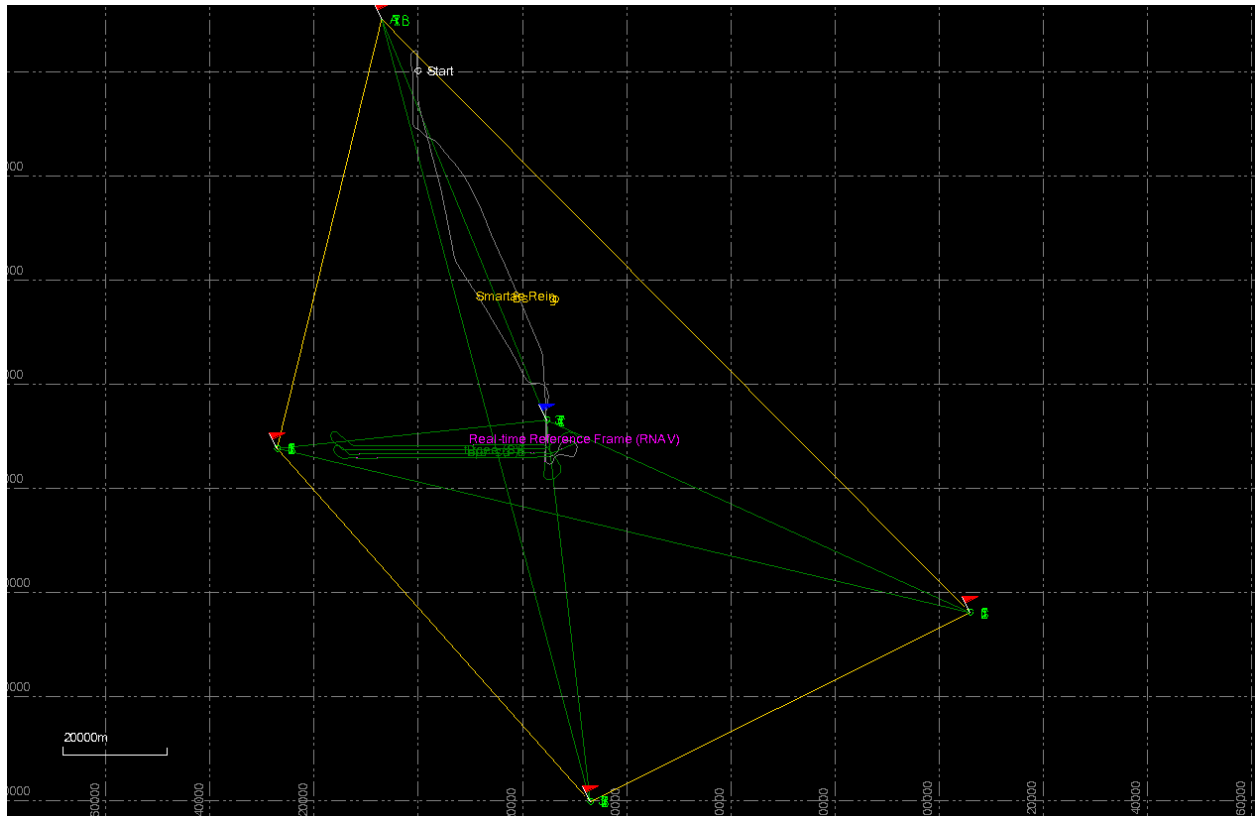
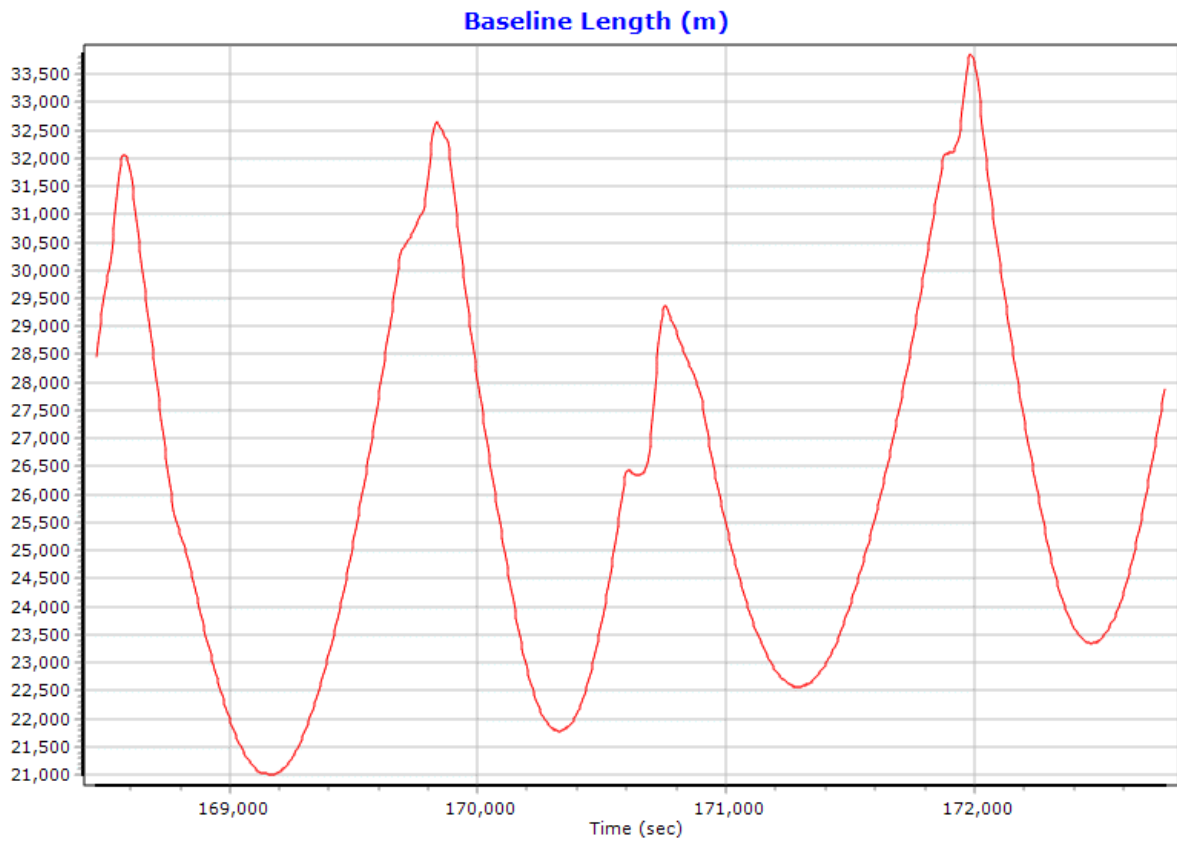


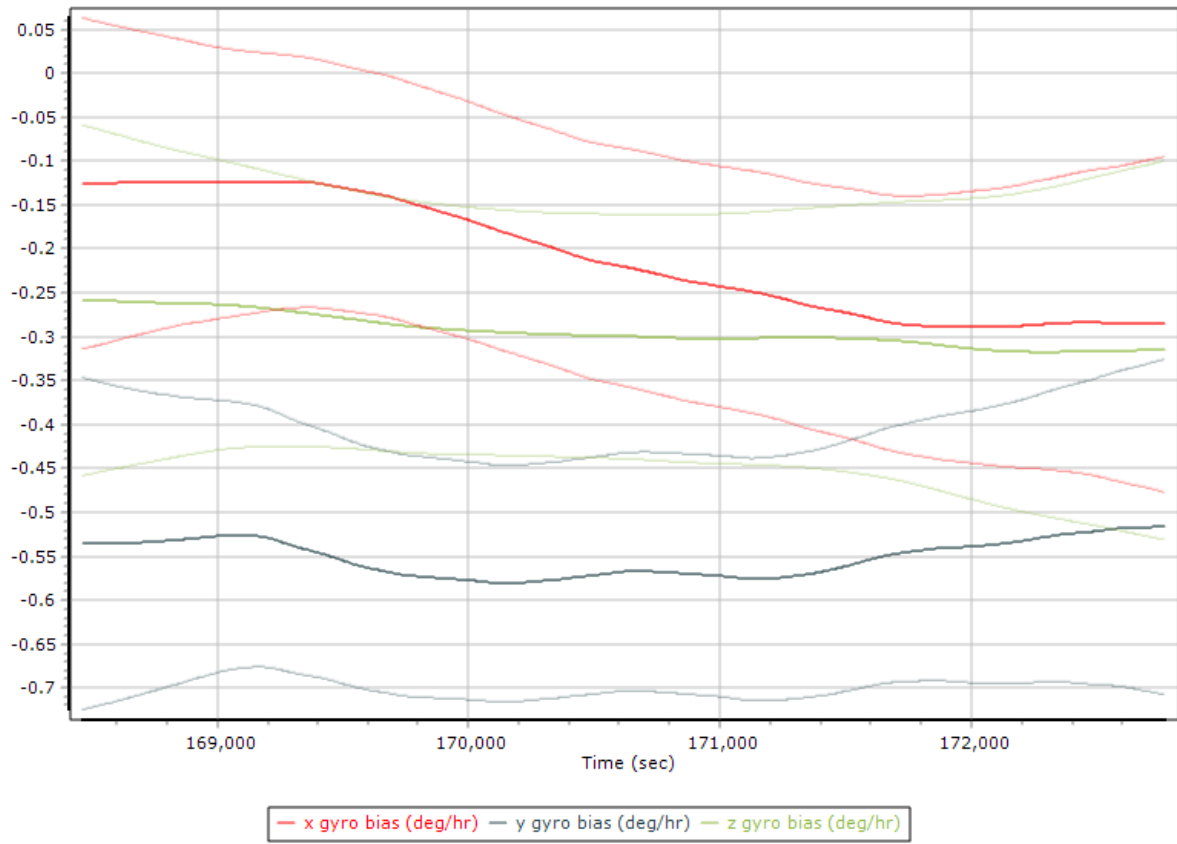
UNB18036A

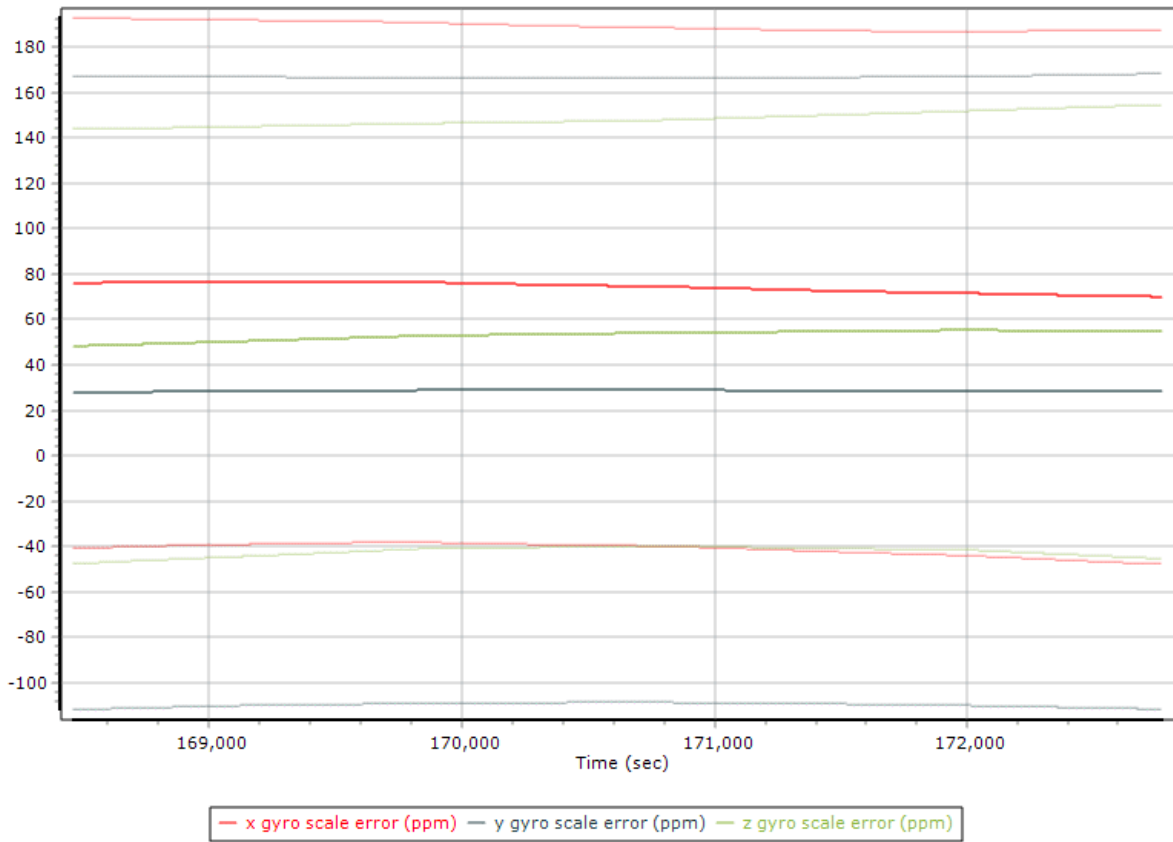












Project Settings [X]

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

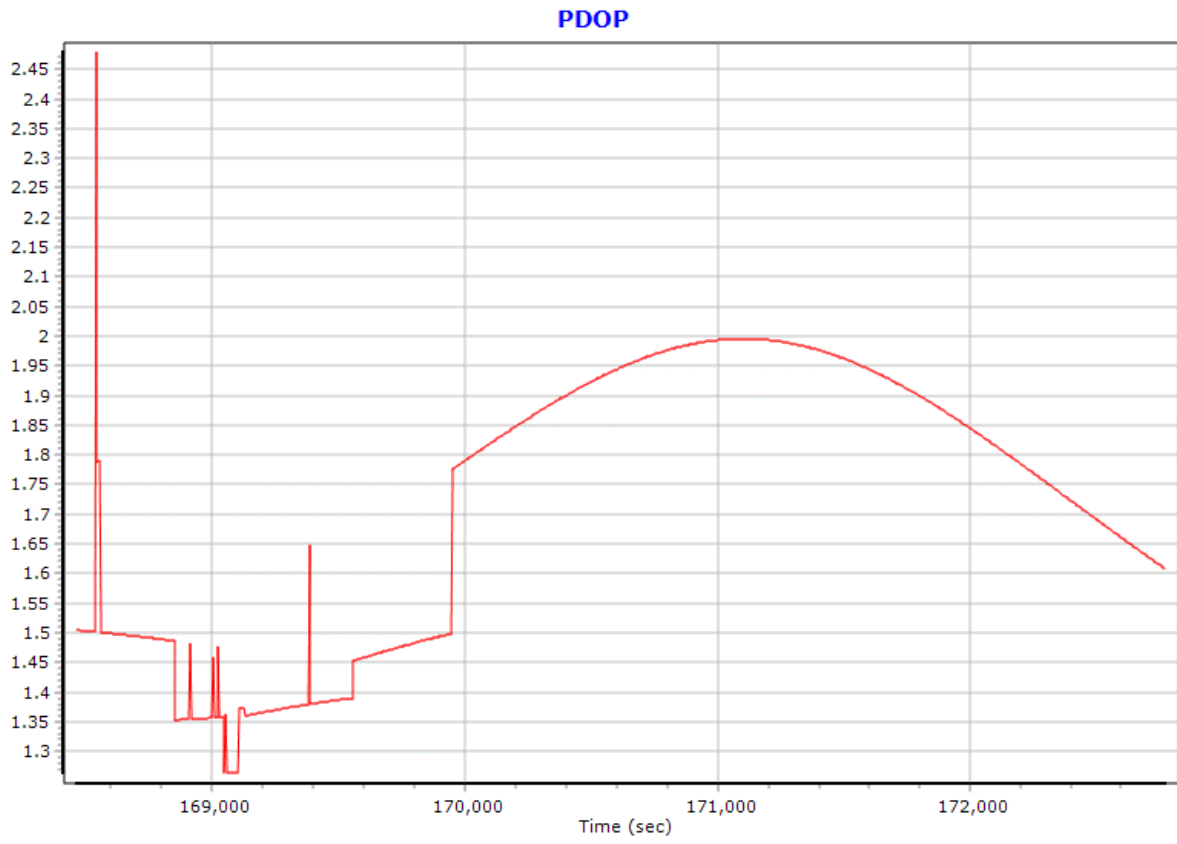
Aircraft to Reference Mounting Angles

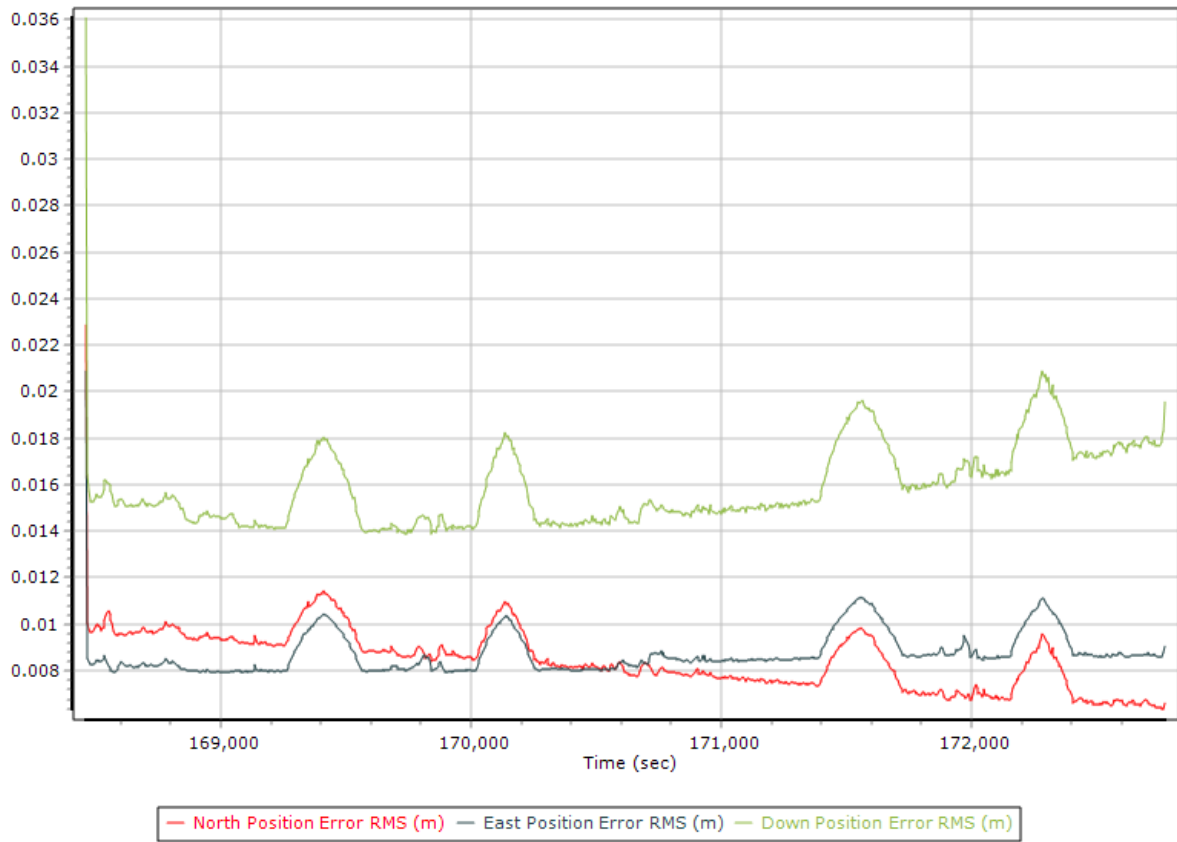
X:

Y:

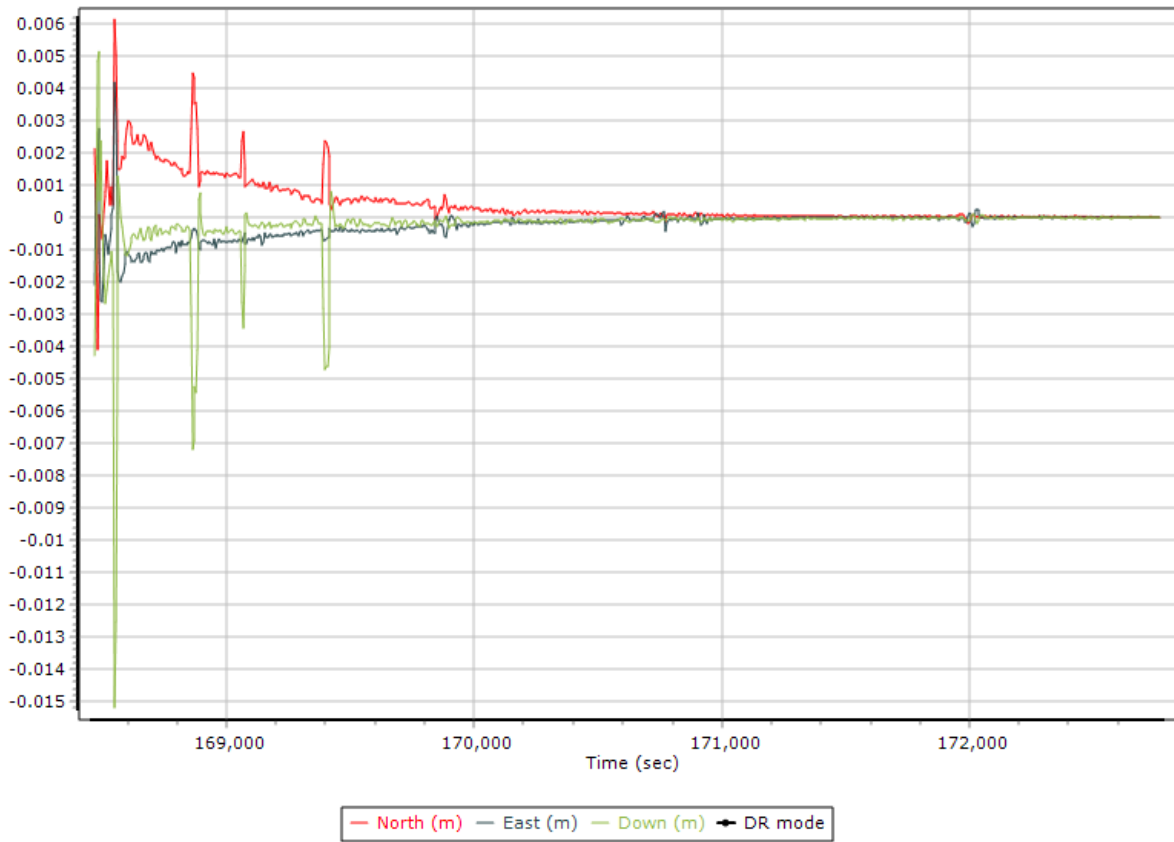
Z:

OK Cancel









Project Settings

- 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: 168461.580
End: 172775.739

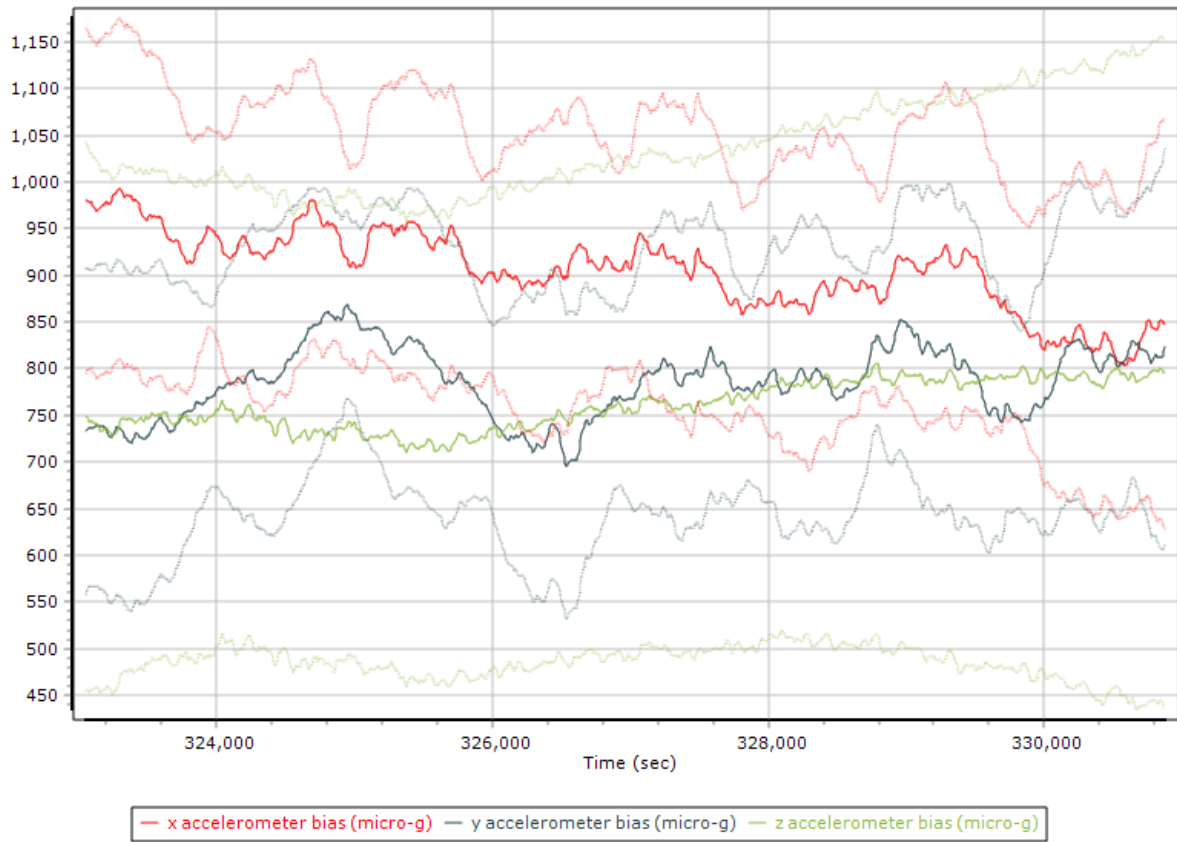
Entire time interval
 Seconds of start week

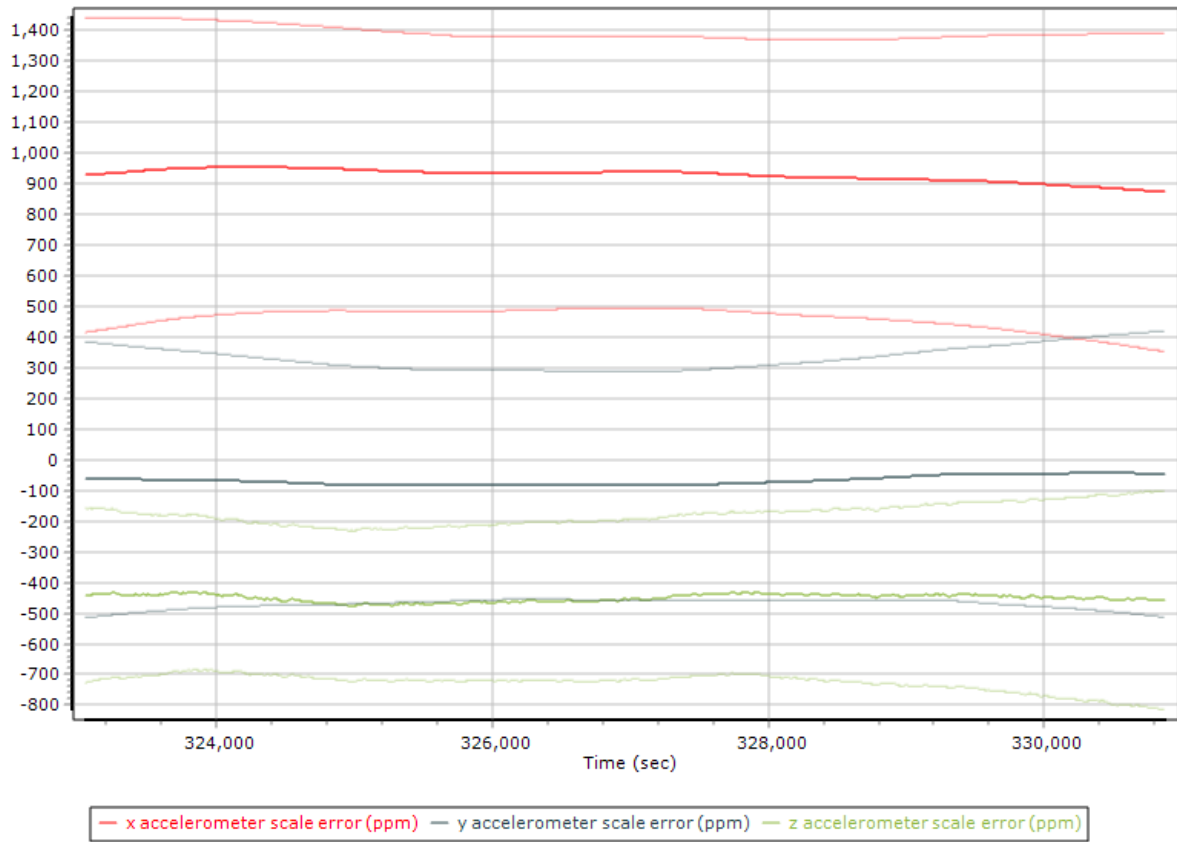
UTC Offset: 18.000

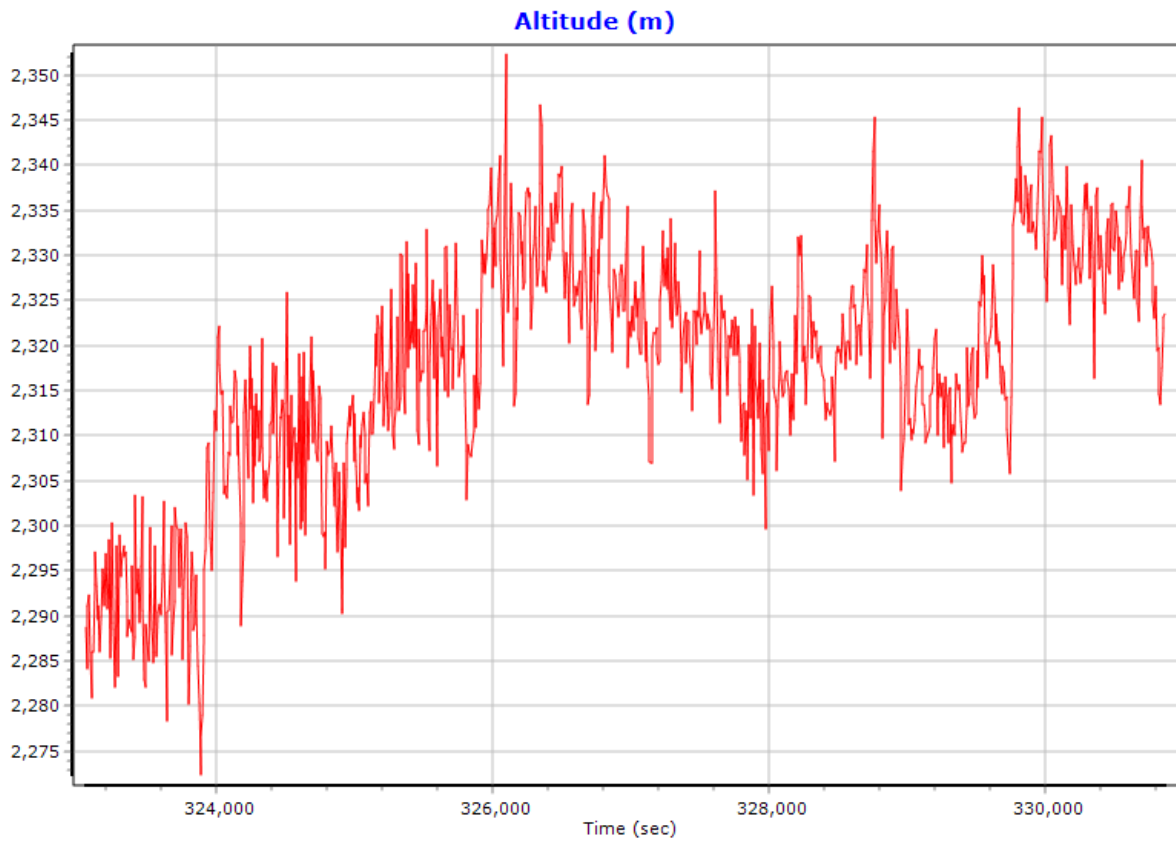
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

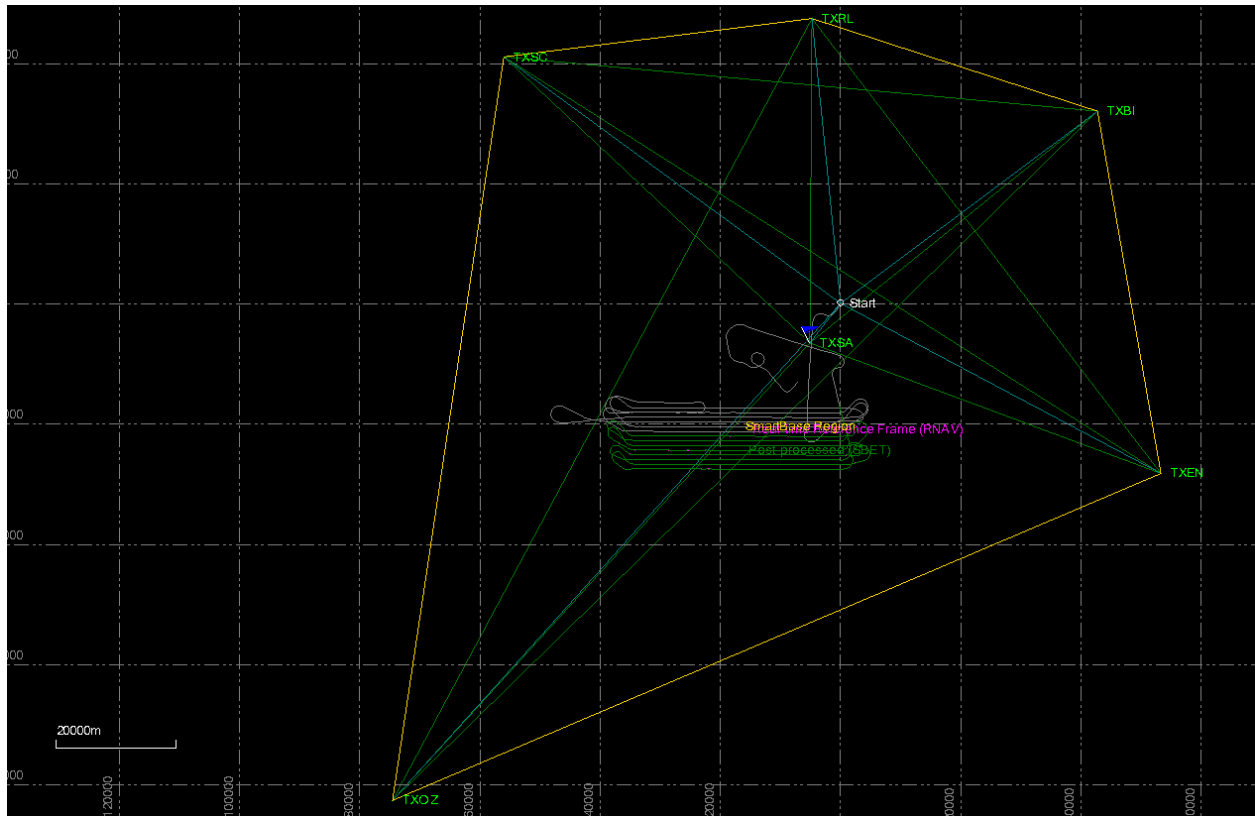
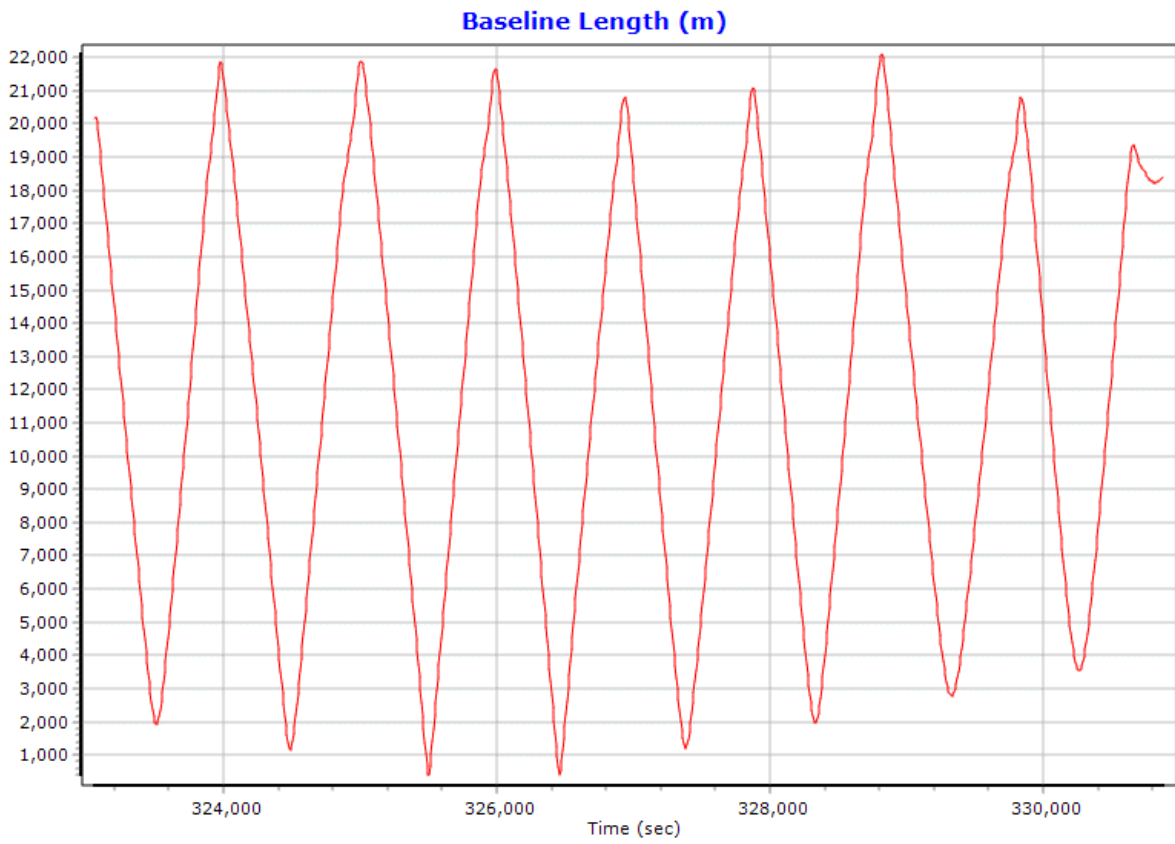
OK Cancel

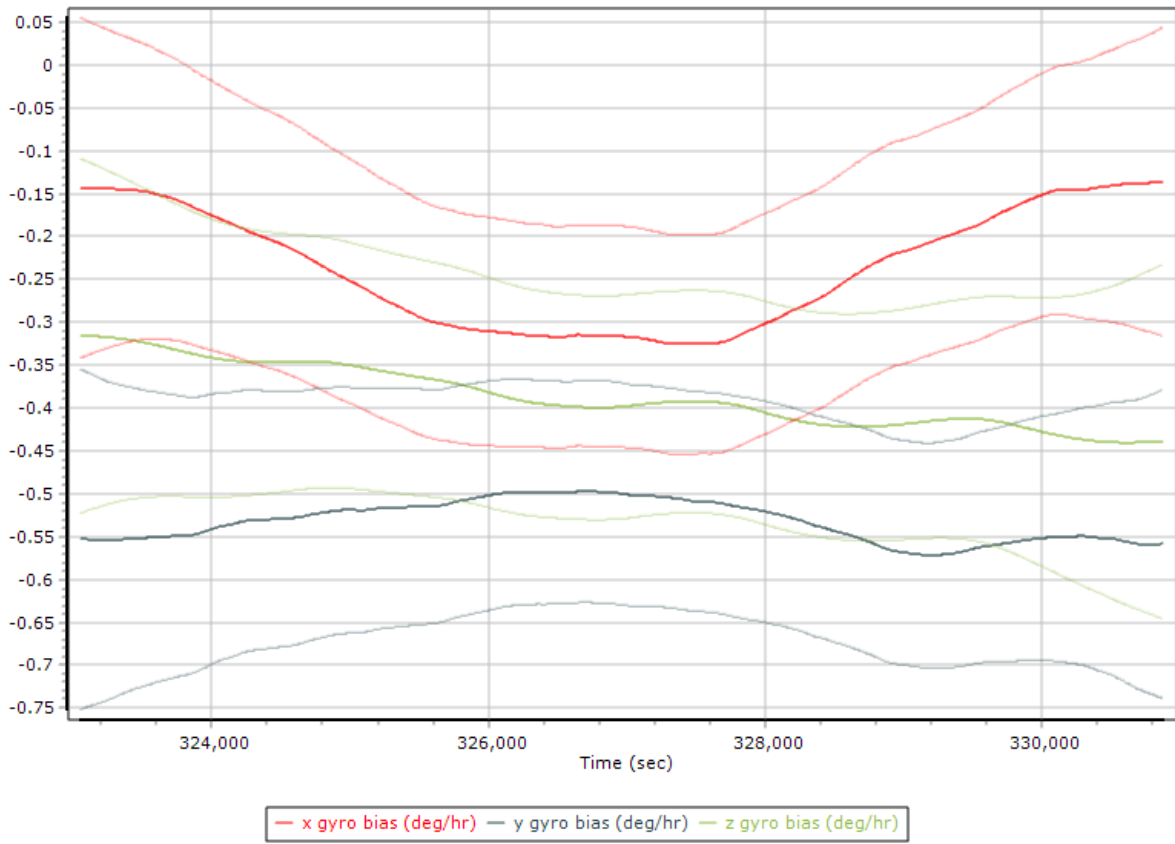
UNB18038A1

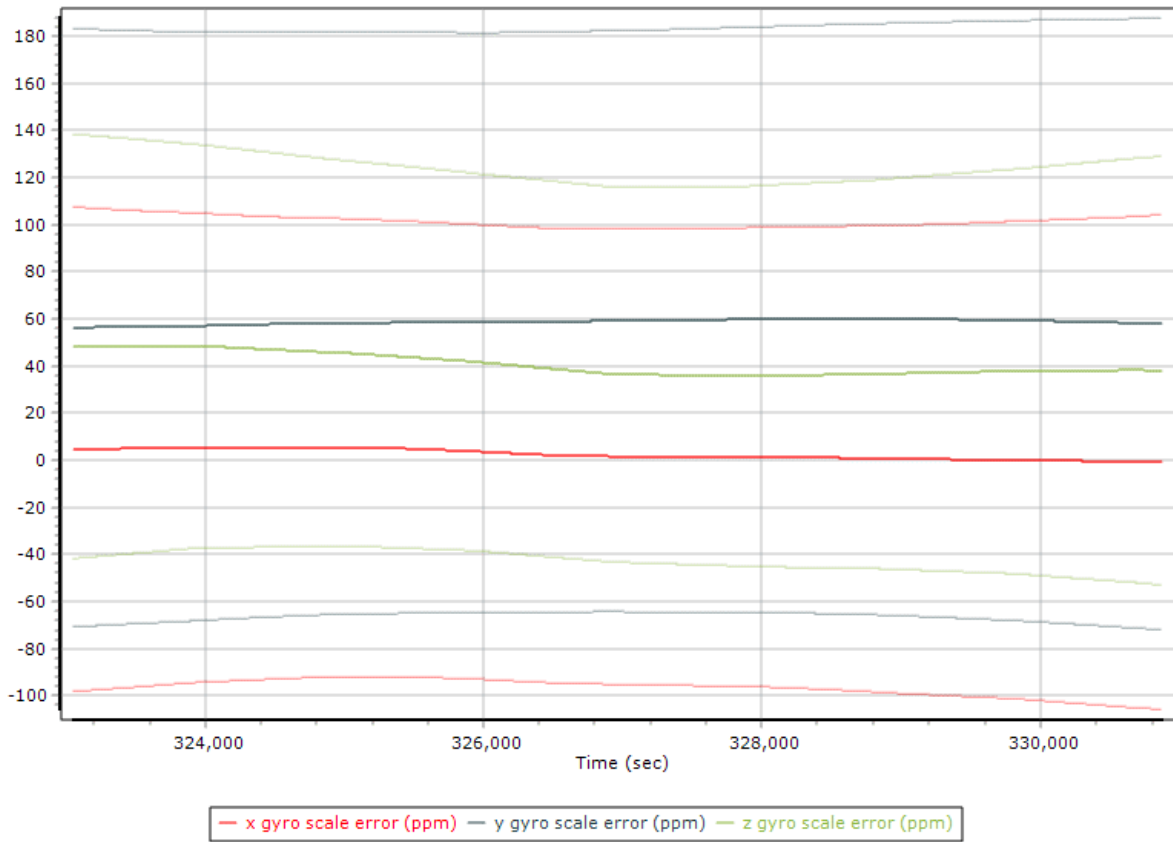












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

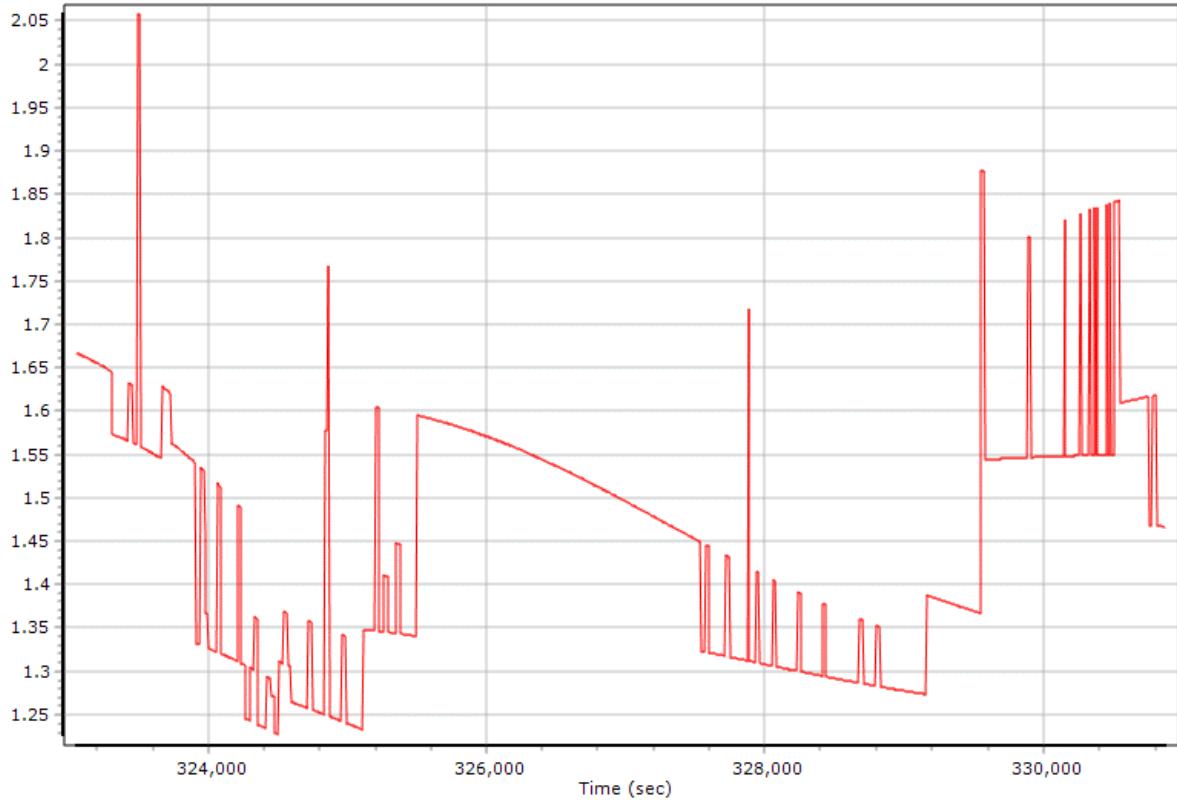
Aircraft to Reference Mounting Angles

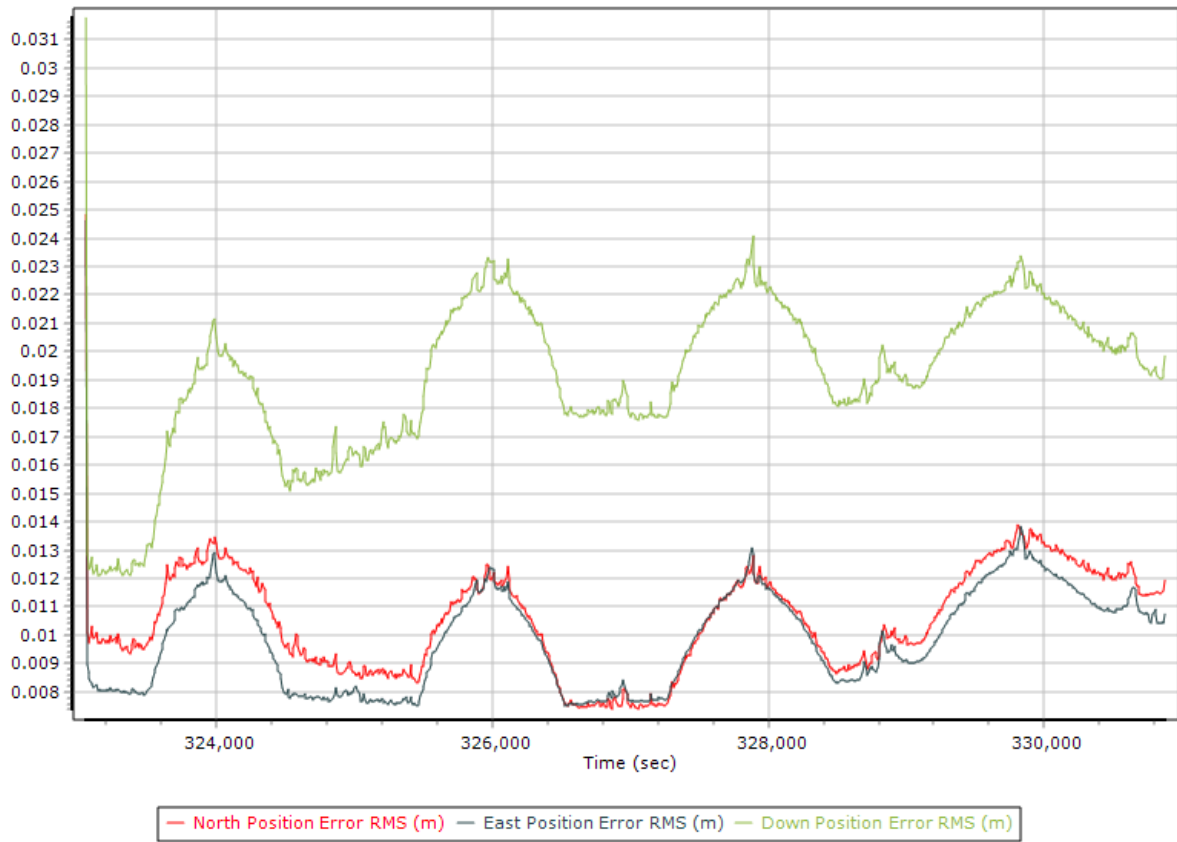
X:

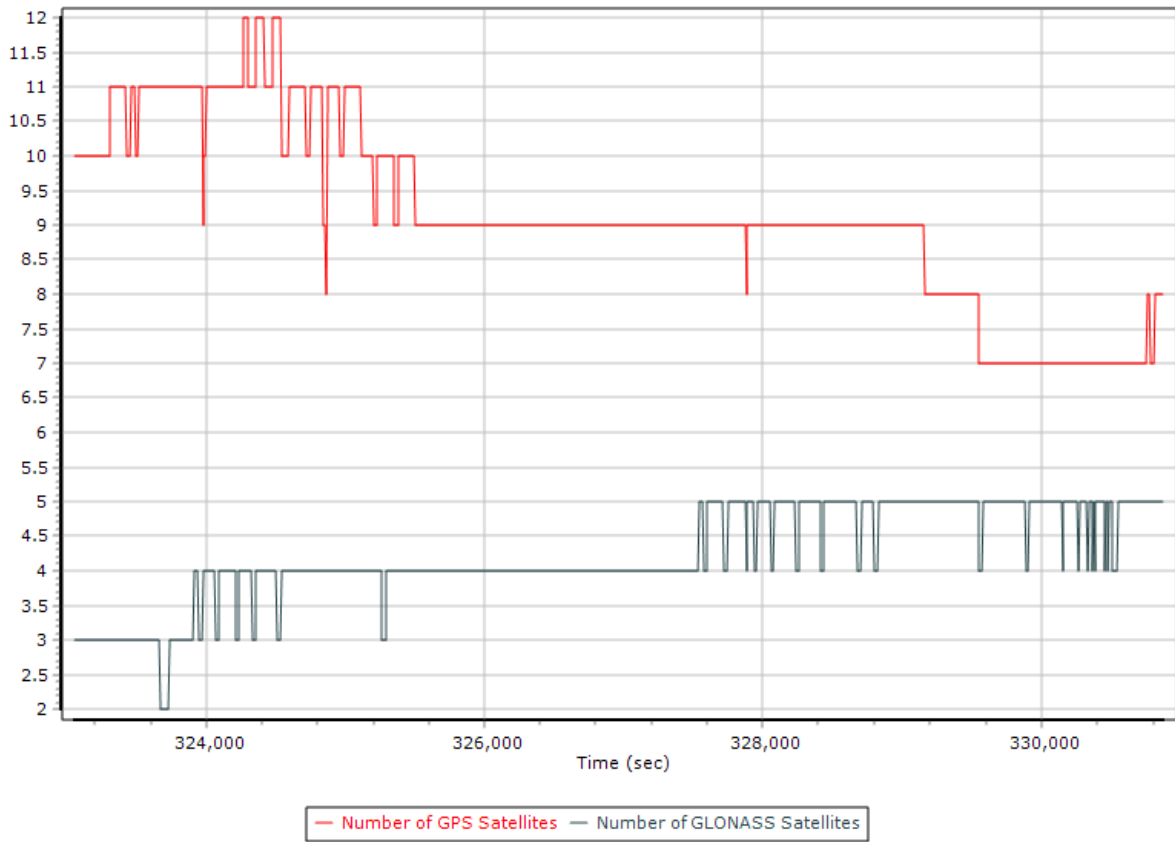
Y:

Z:

PDOP









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: 323054.395
 End: 330883.877

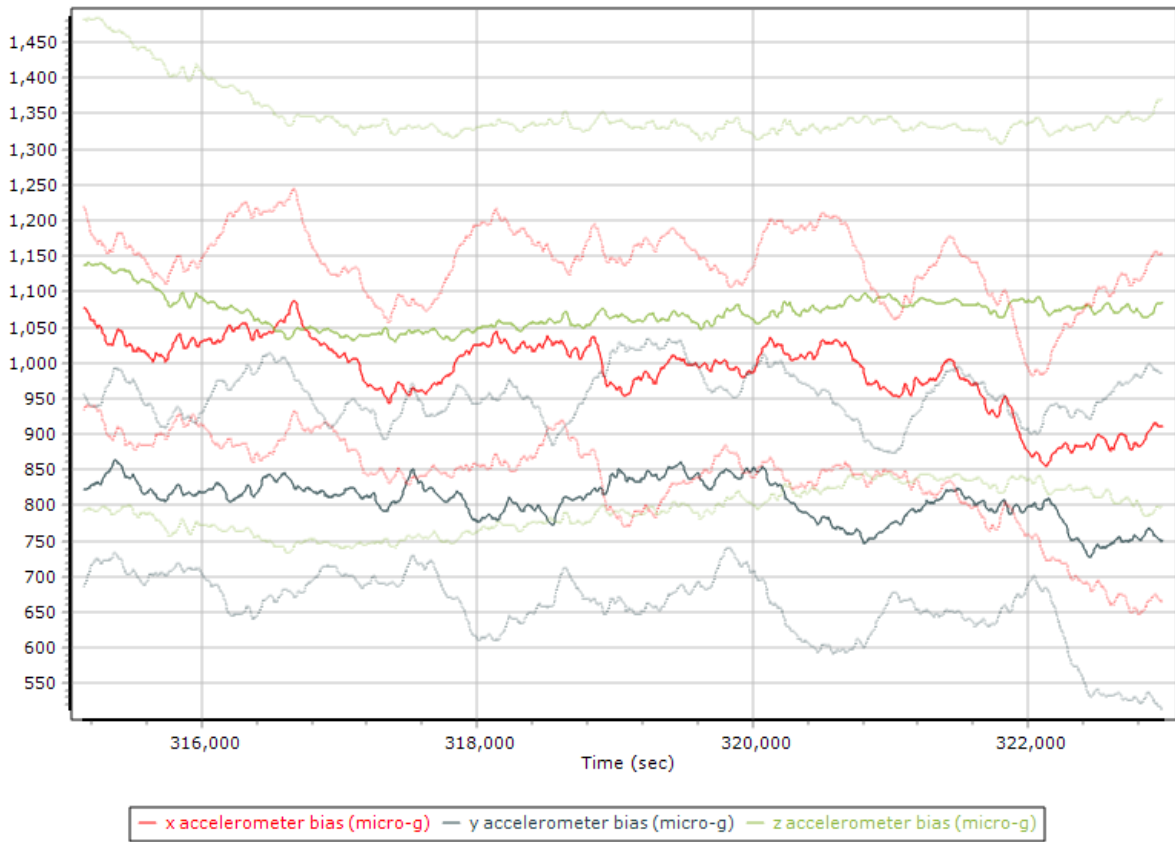
Entire time interval
 Seconds of start week

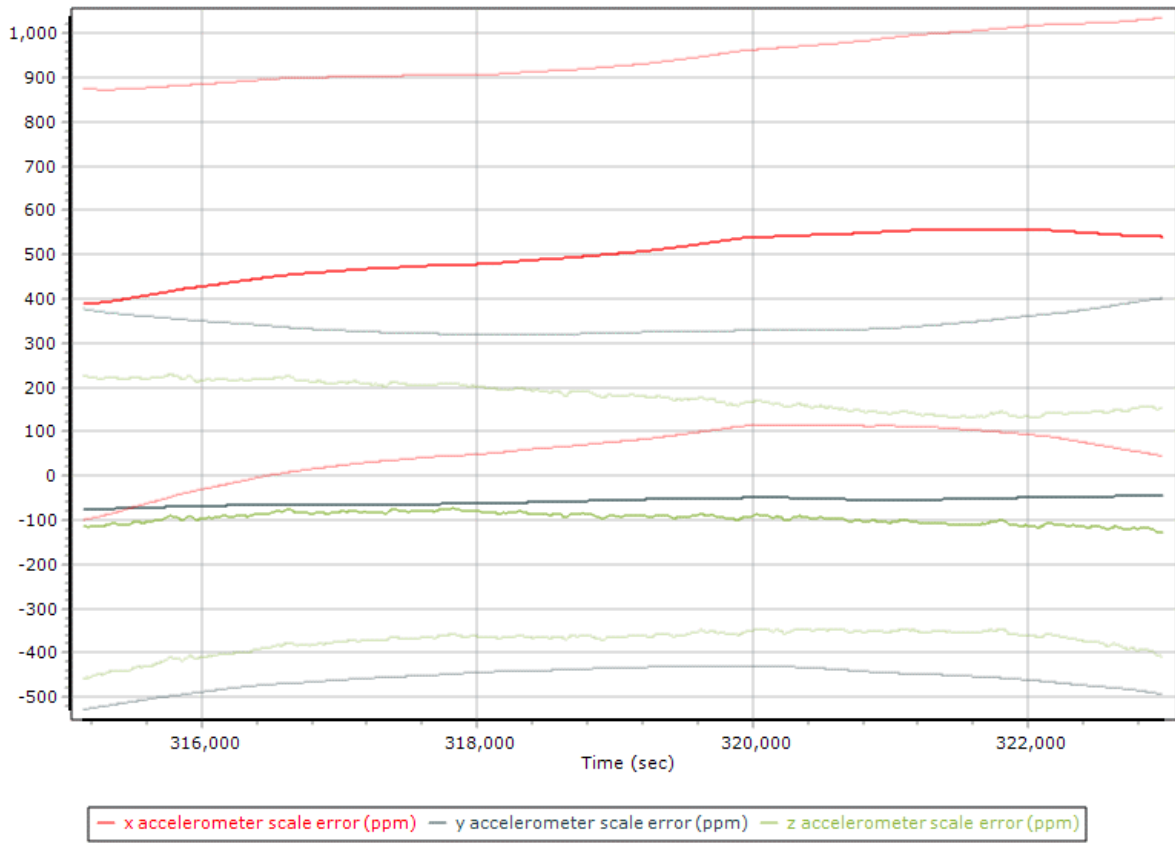
UTC Offset: 18.000

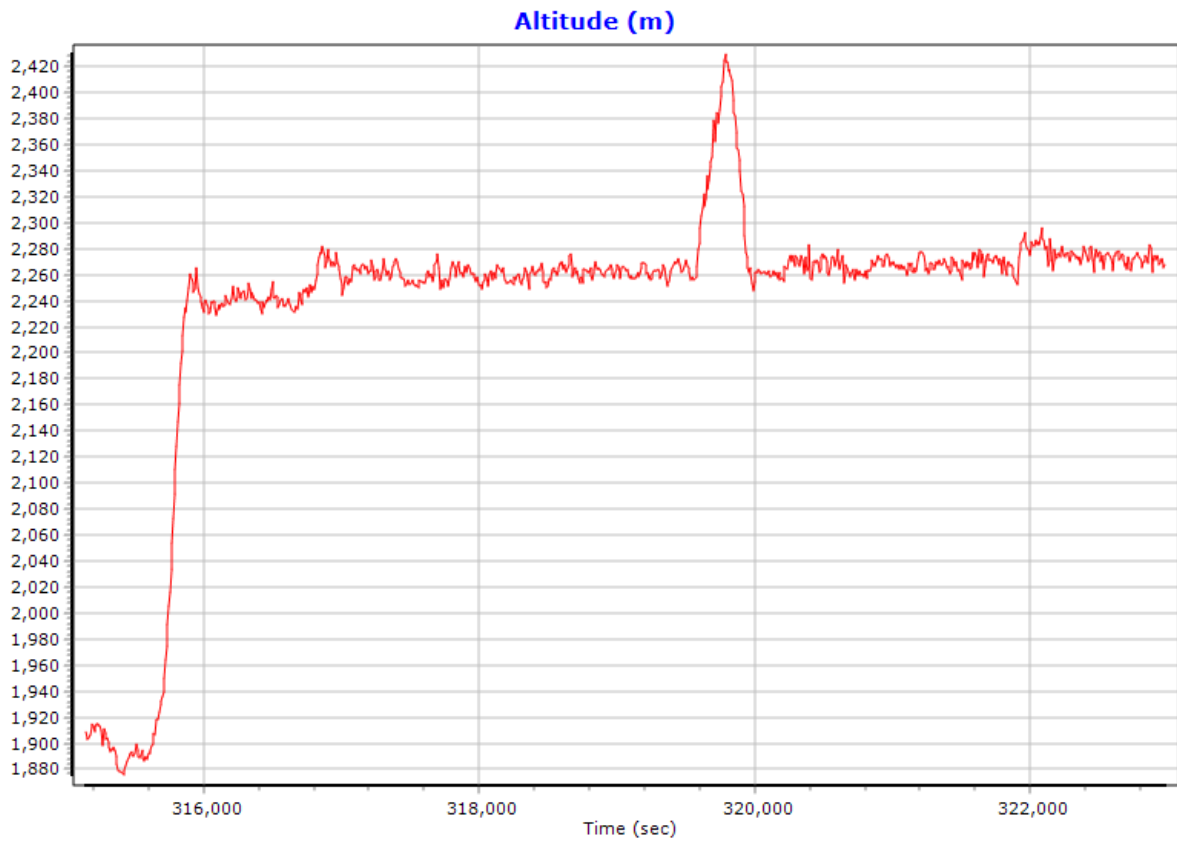
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

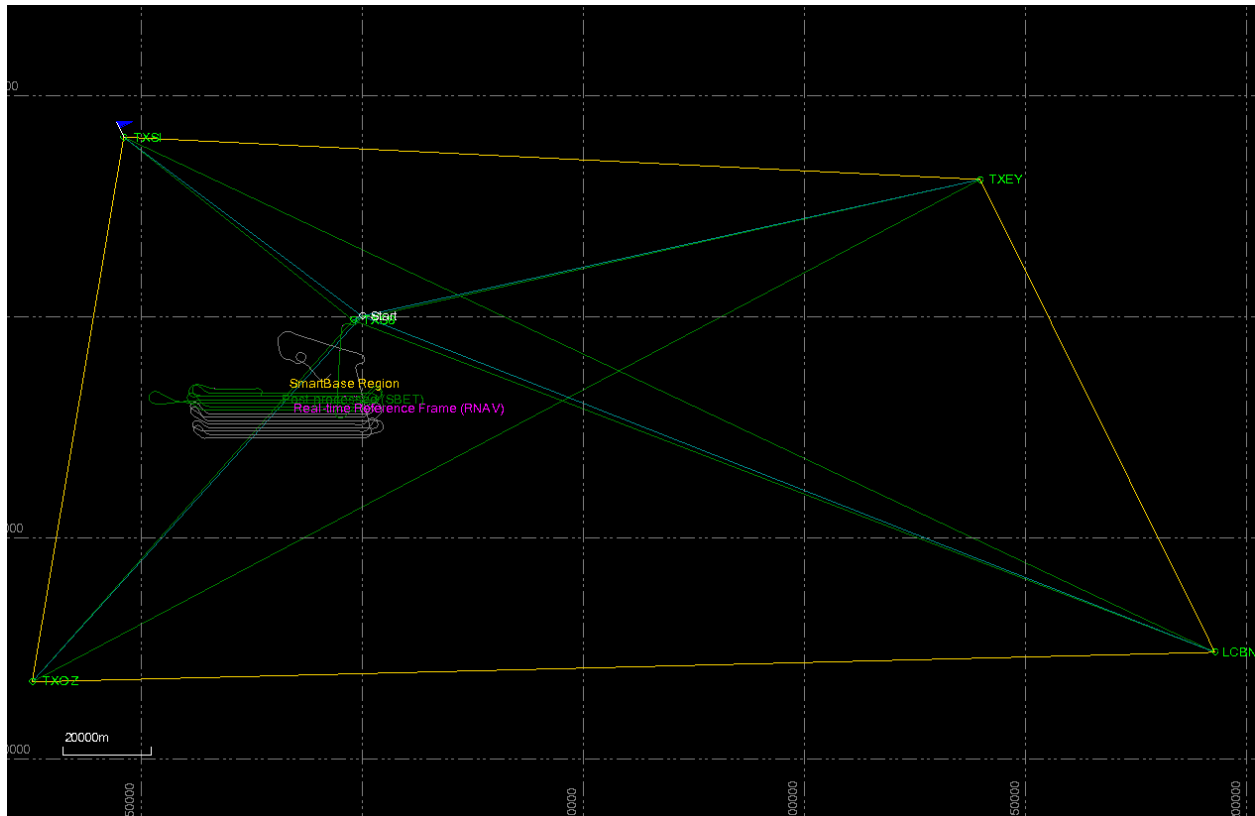
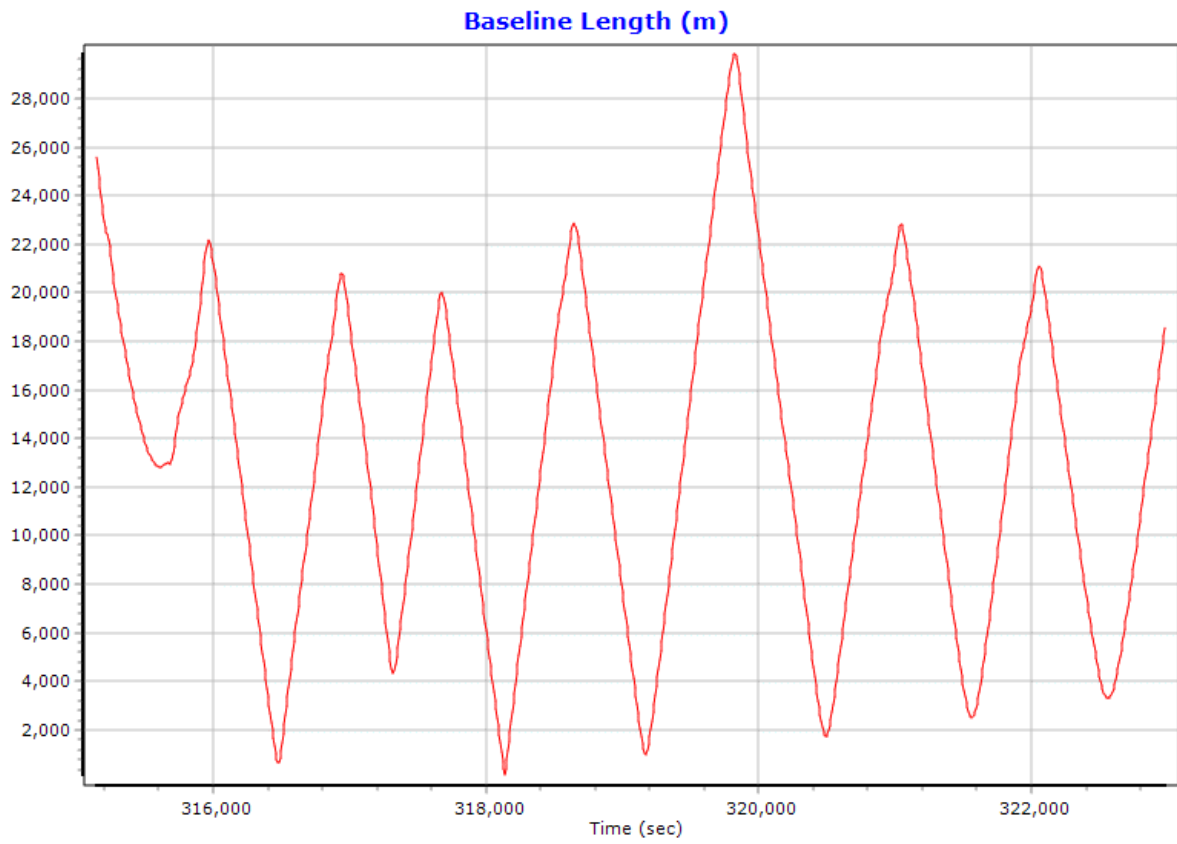
OK Cancel

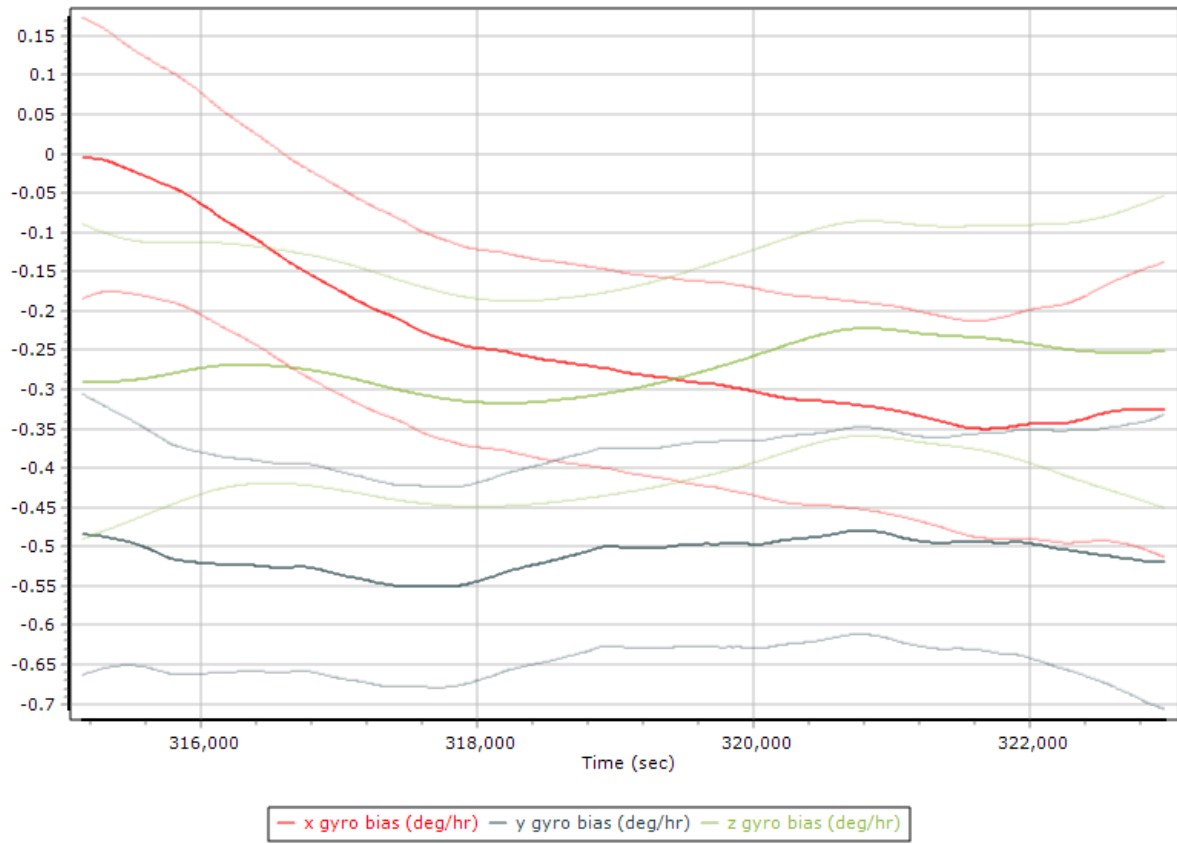
UNB18038A2

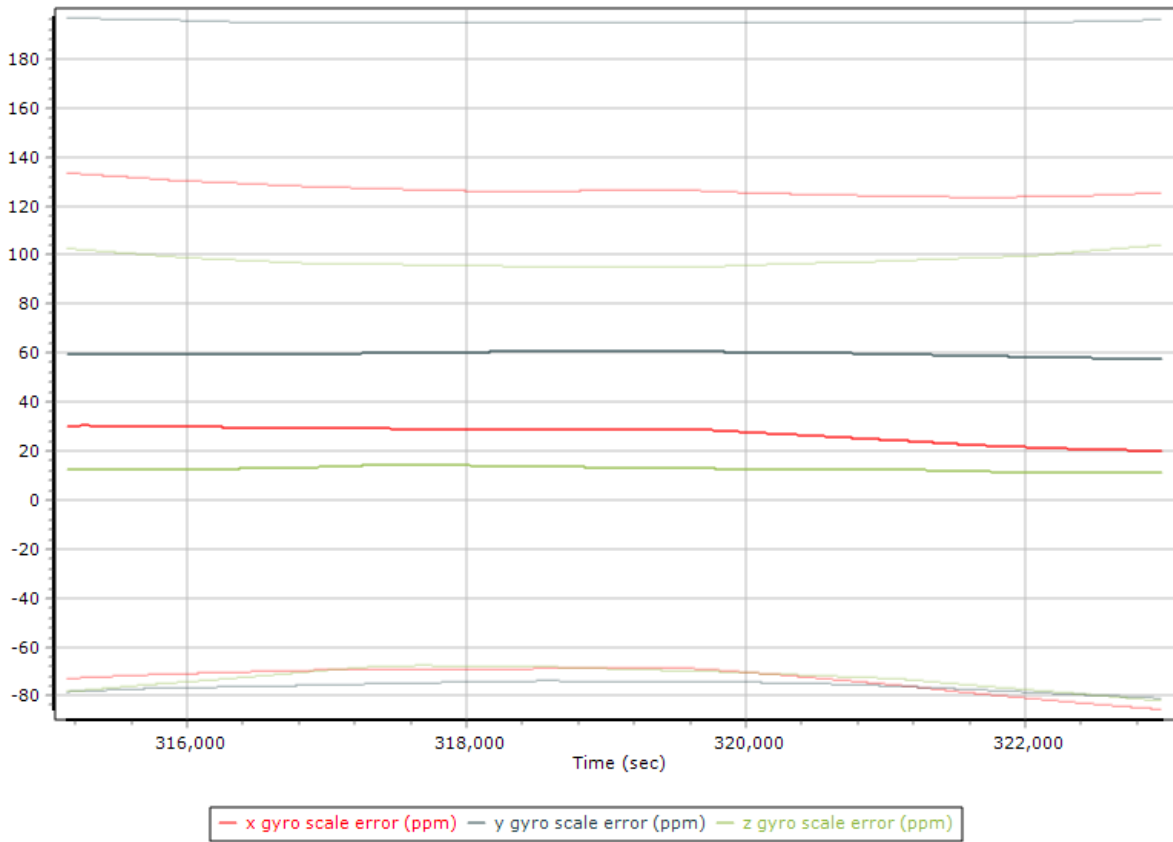












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

Aircraft to Reference Mounting Angles

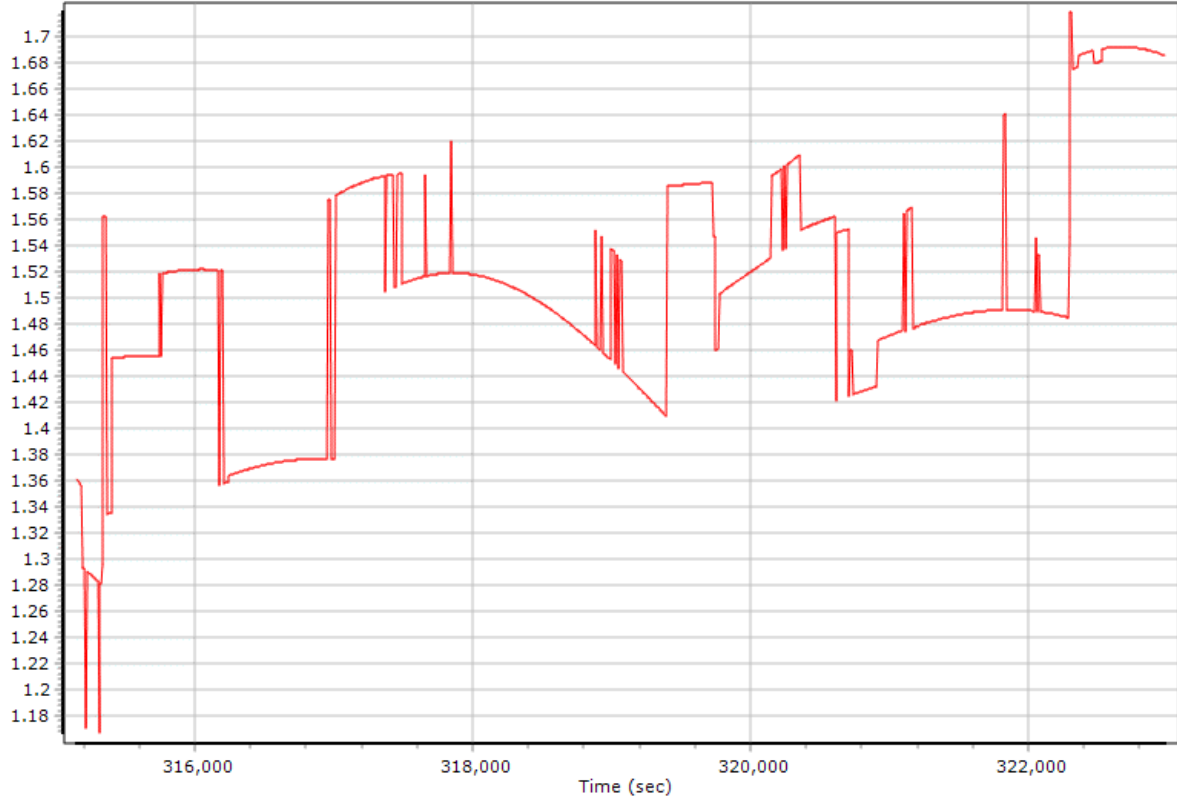
X:

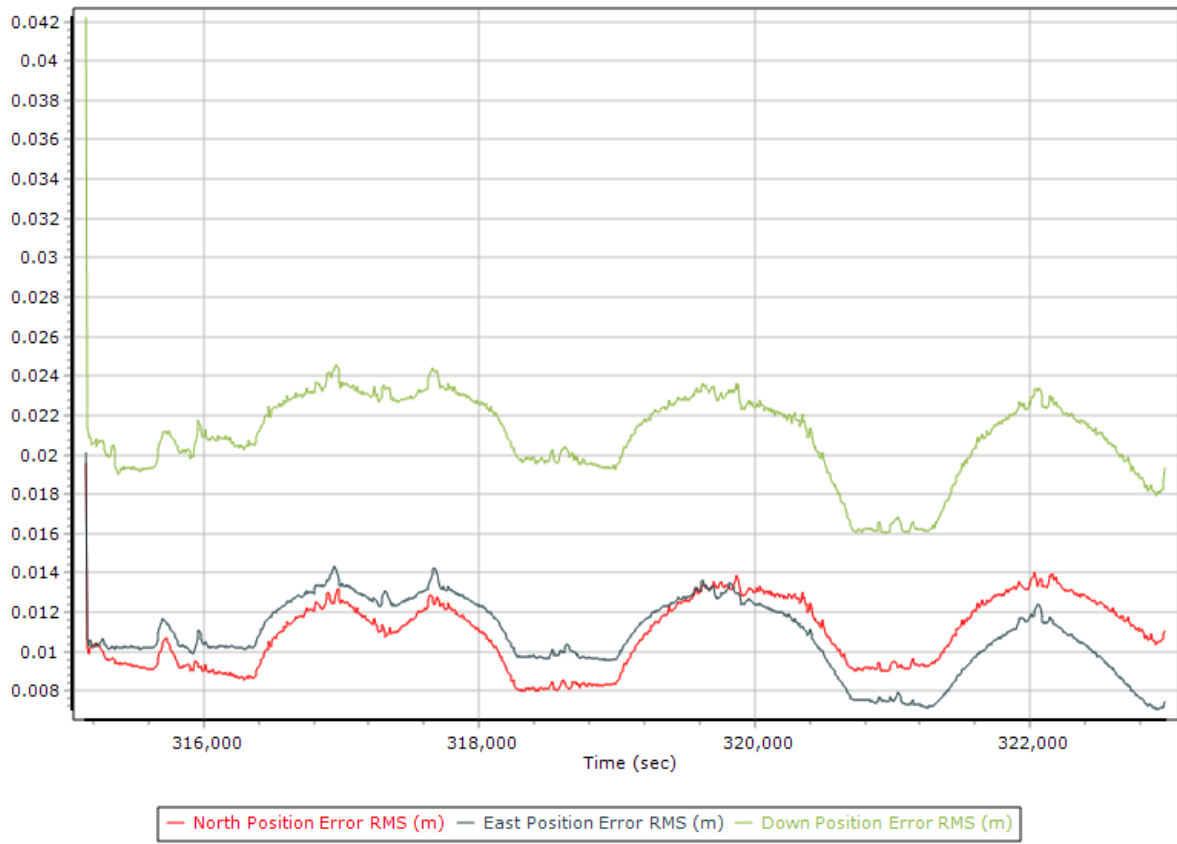
Y:

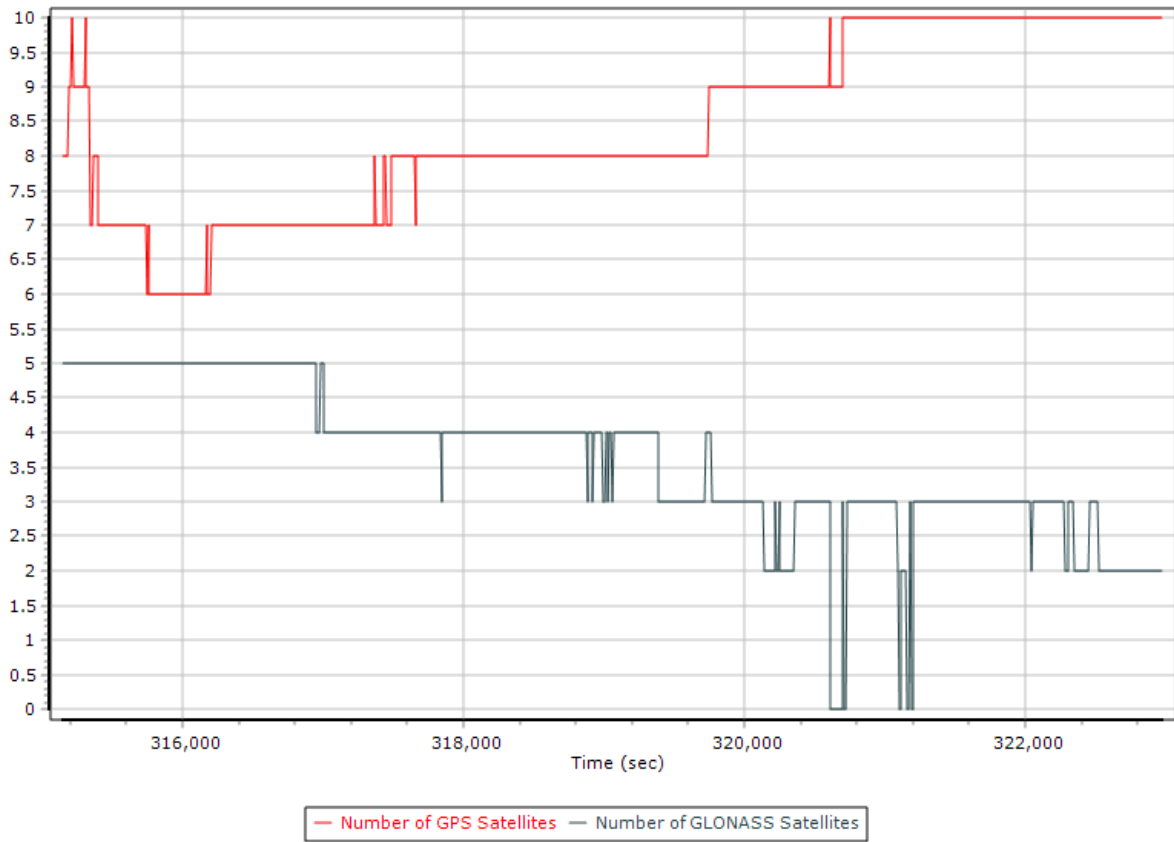
Z:

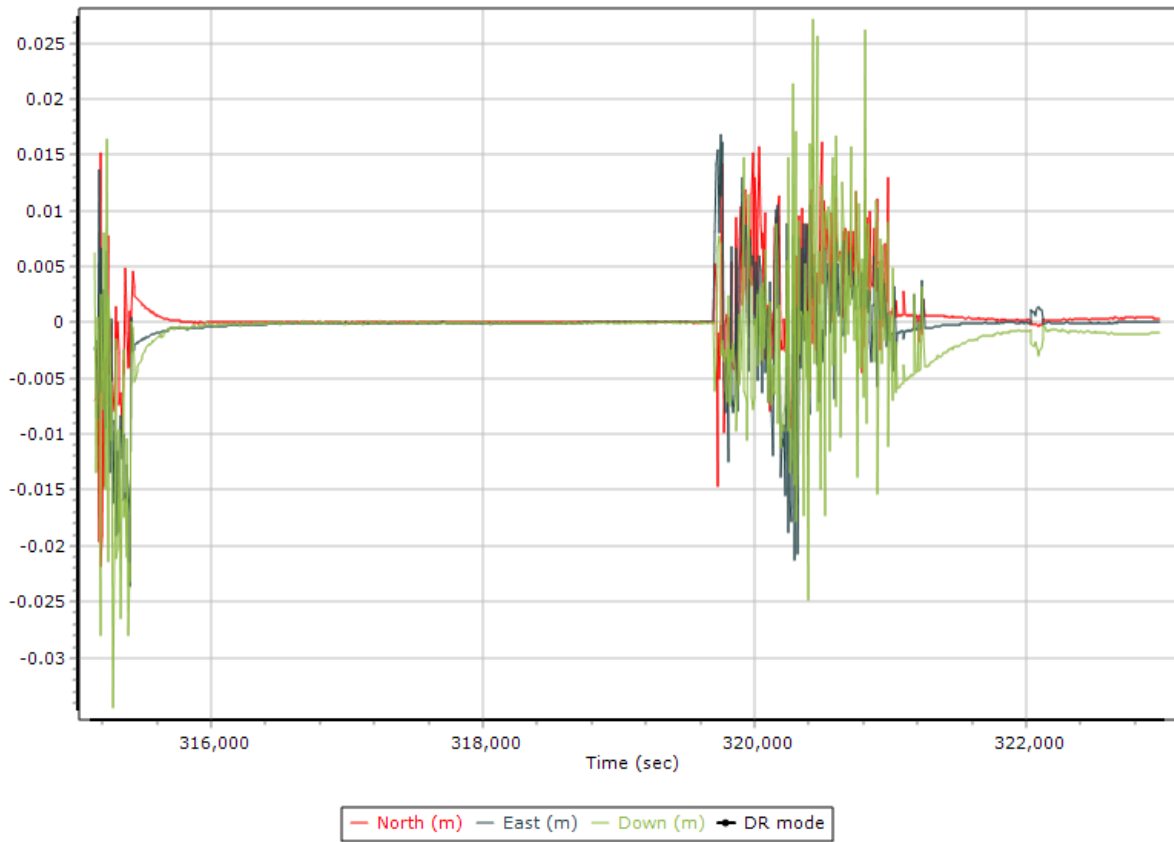
OK Cancel

PDOP









Project Settings [X]

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

Timing

Start: 315142.099
 End: 322989.393

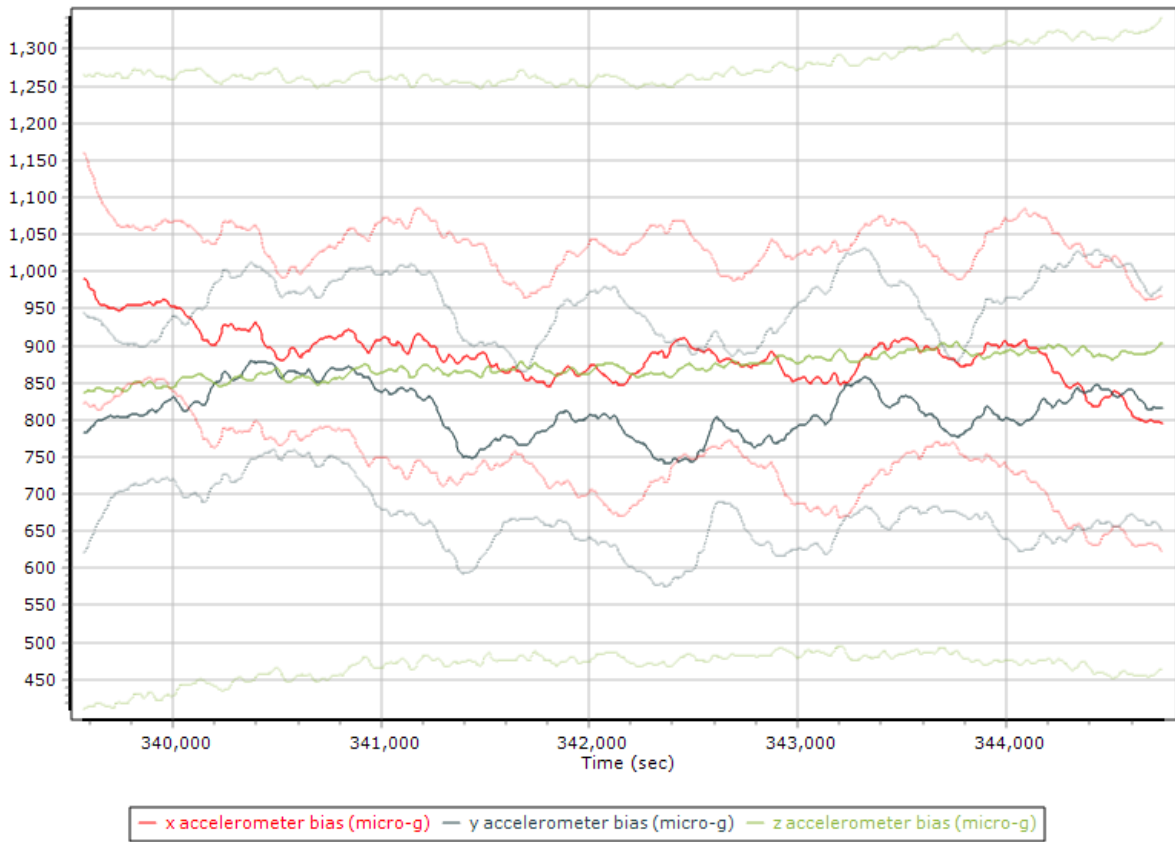
Entire time interval
 Seconds of start week

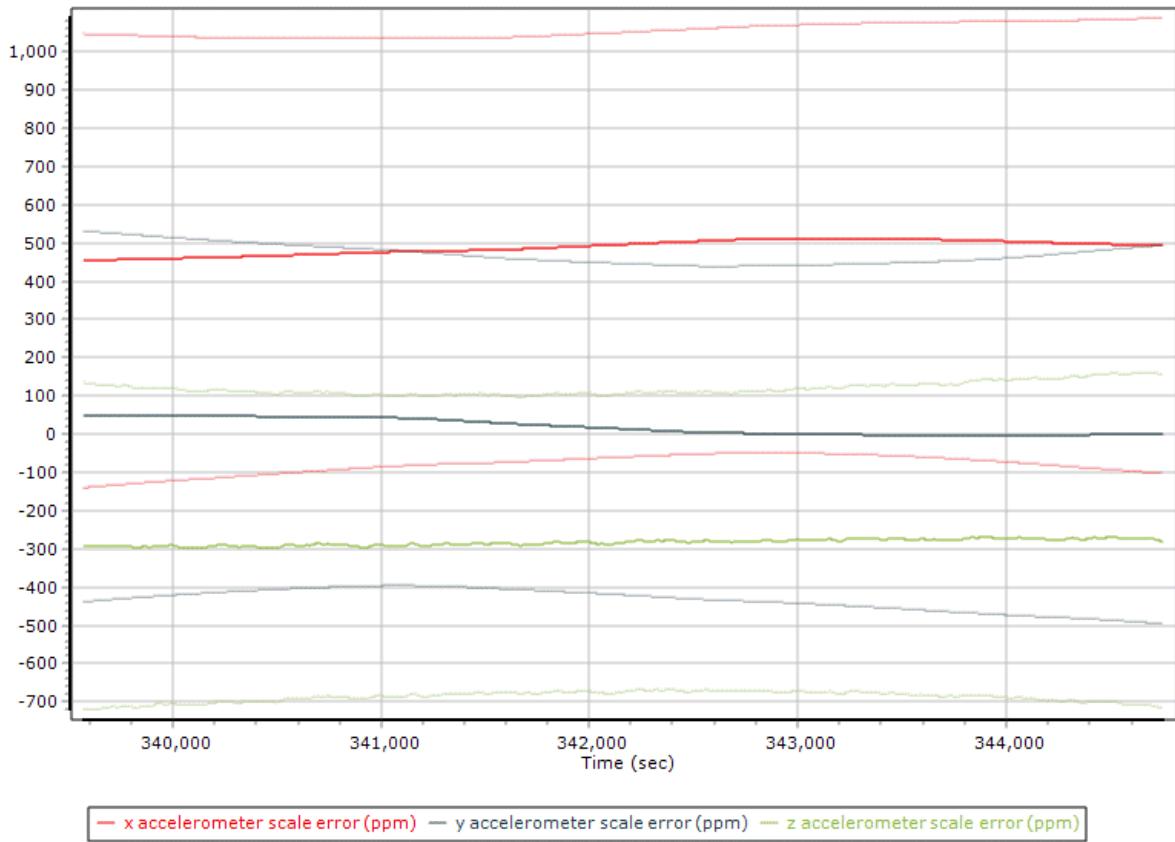
UTC Offset: 18.000

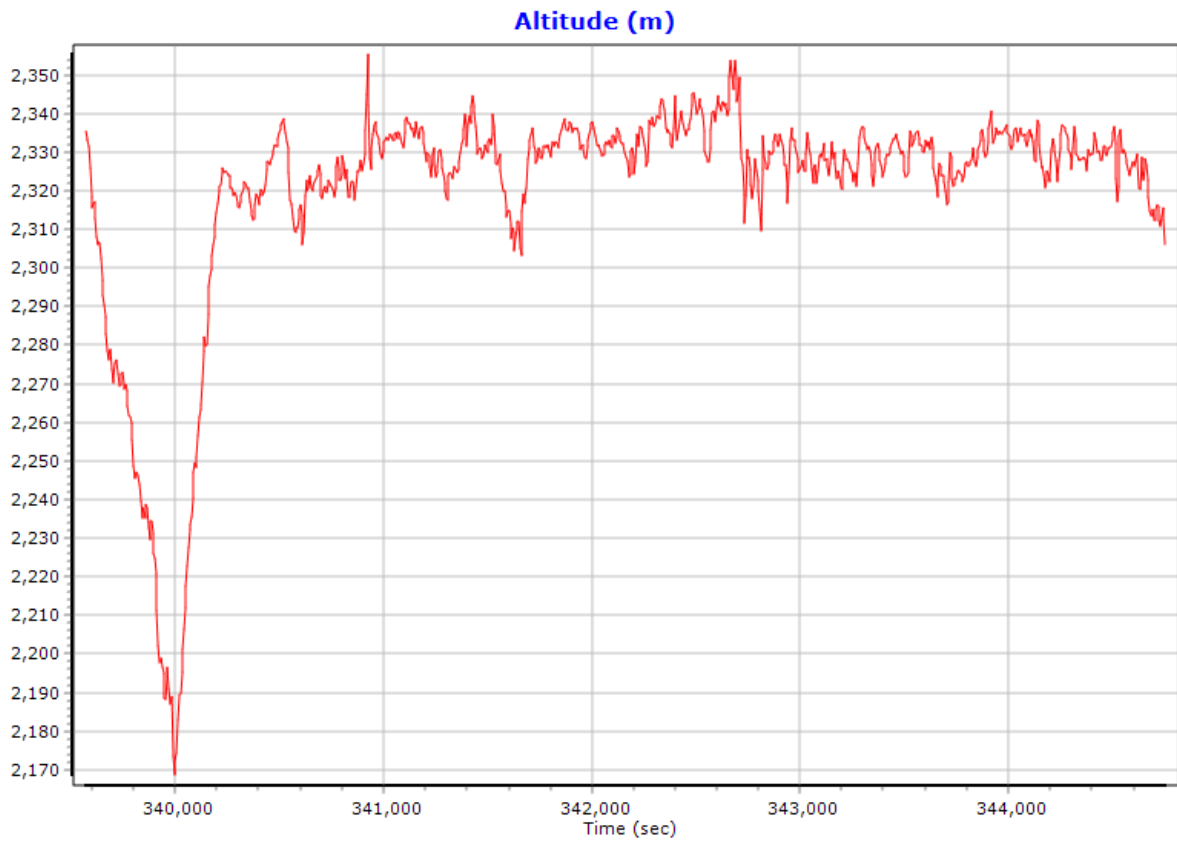
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

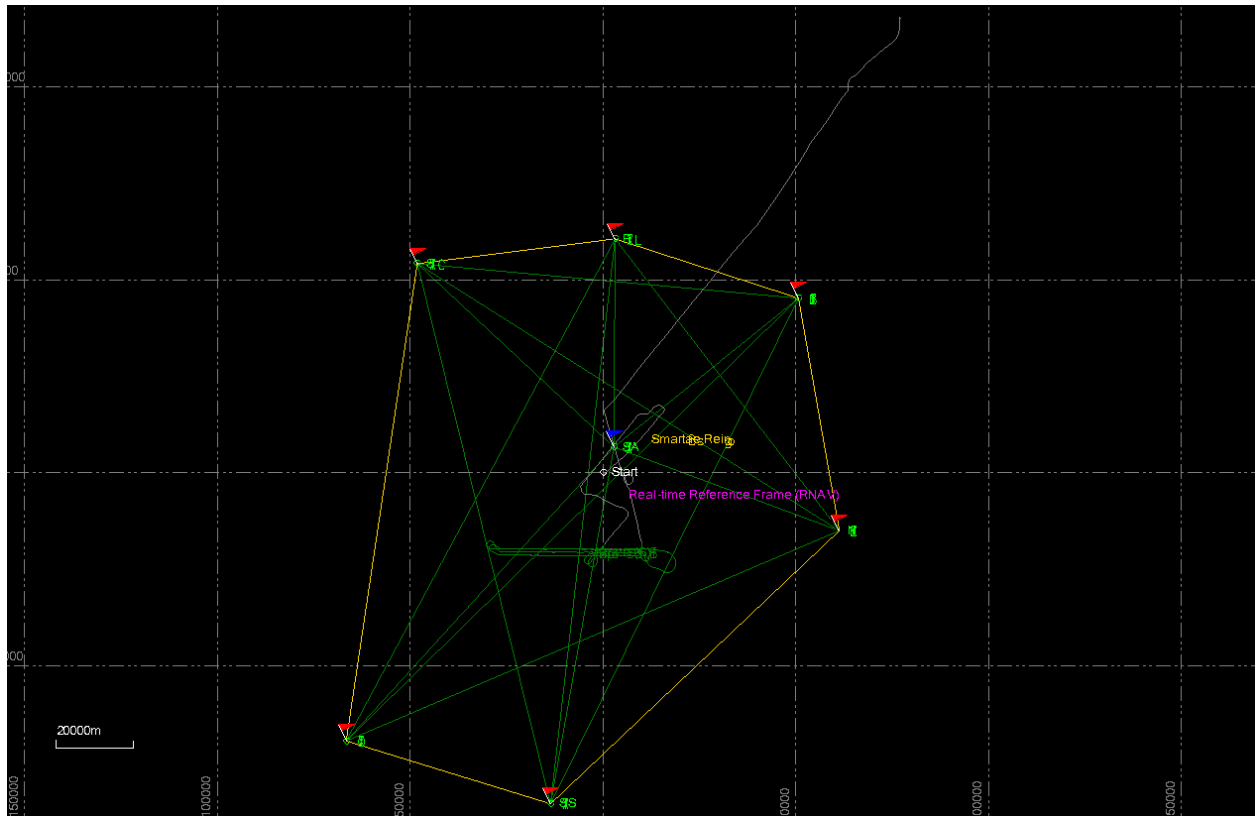
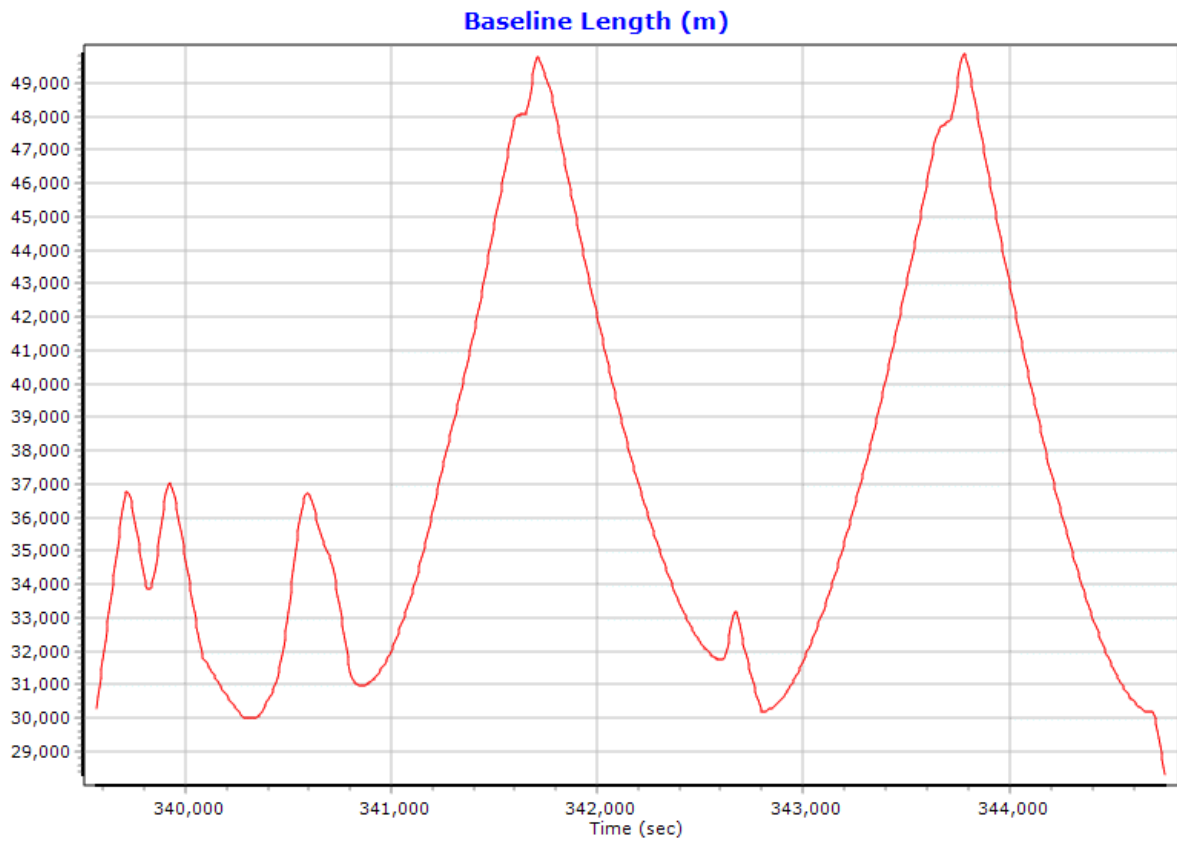
OK Cancel

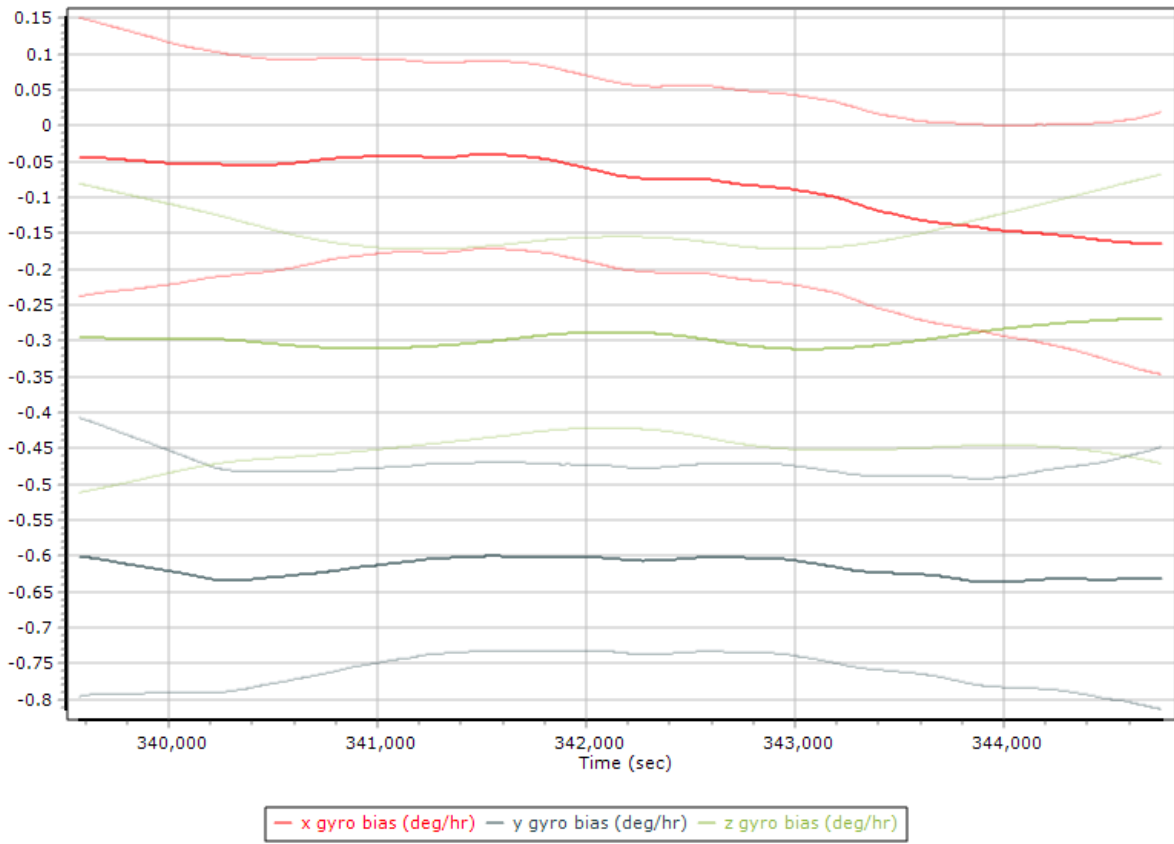
UNB18038B

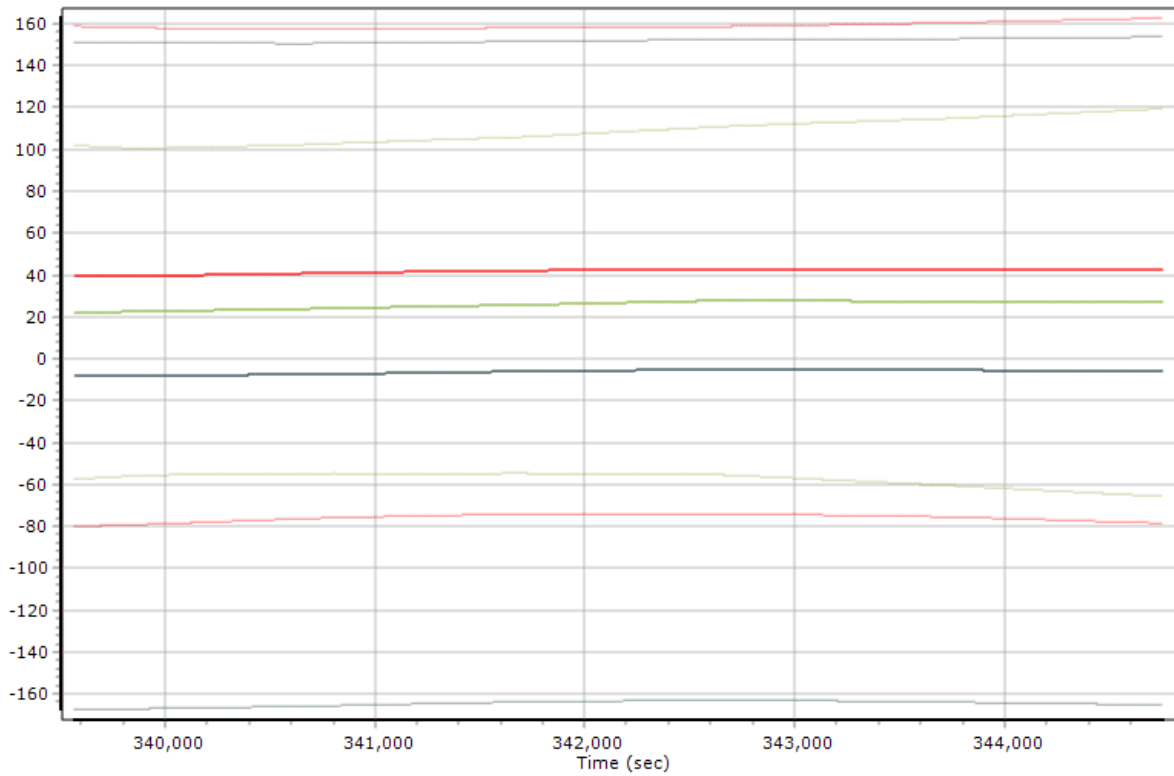












— x gyro scale error (ppm) — y gyro scale error (ppm) — z gyro scale error (ppm)

Project Settings ✕

- General Information
- Units
- View
- Rover Import
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 - Timing
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- Export
- Camera
- LiDAR
- SAR

Reference to IMU Lever Arm

X

Y

Z

Reference to IMU Mounting Angles

X

Y

Z

Reference to Primary GNSS Lever Arm

X

Y

Z

Standard Deviation

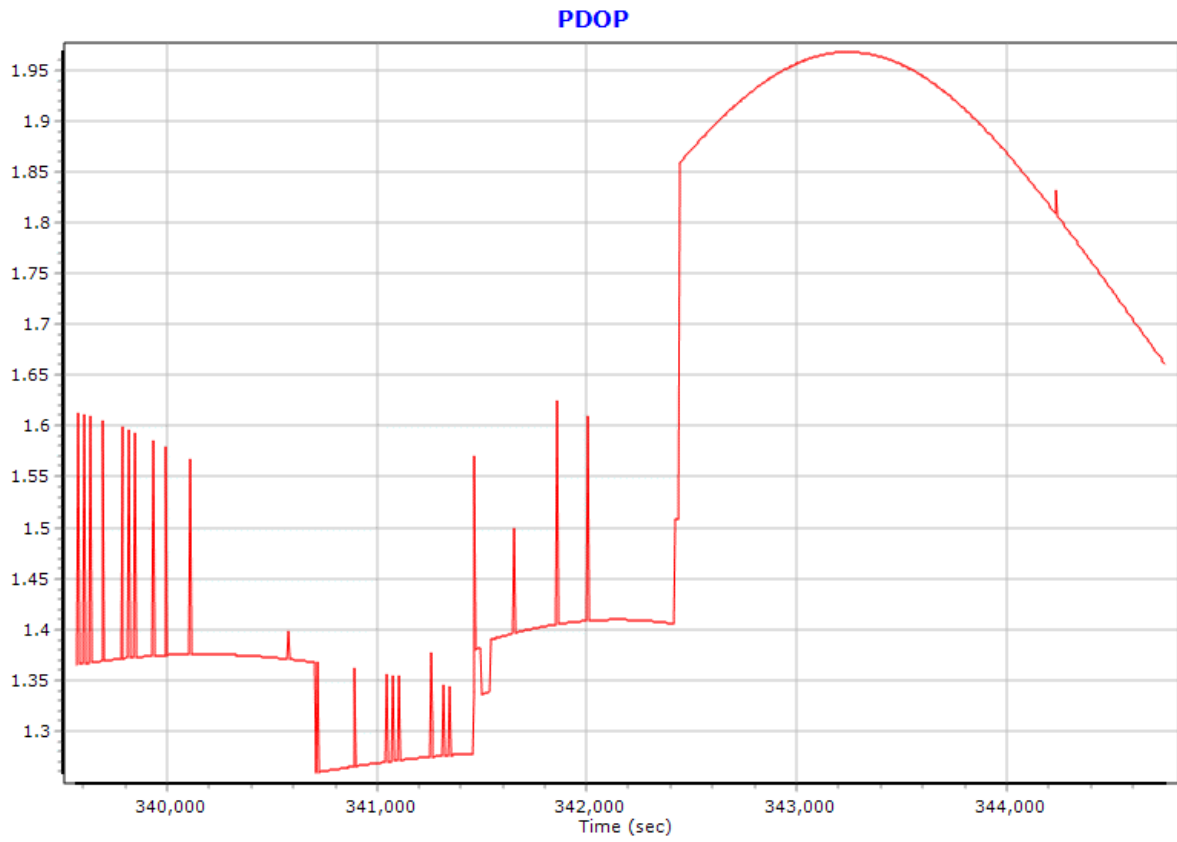
<3cm 10cm 50cm 1m 10m

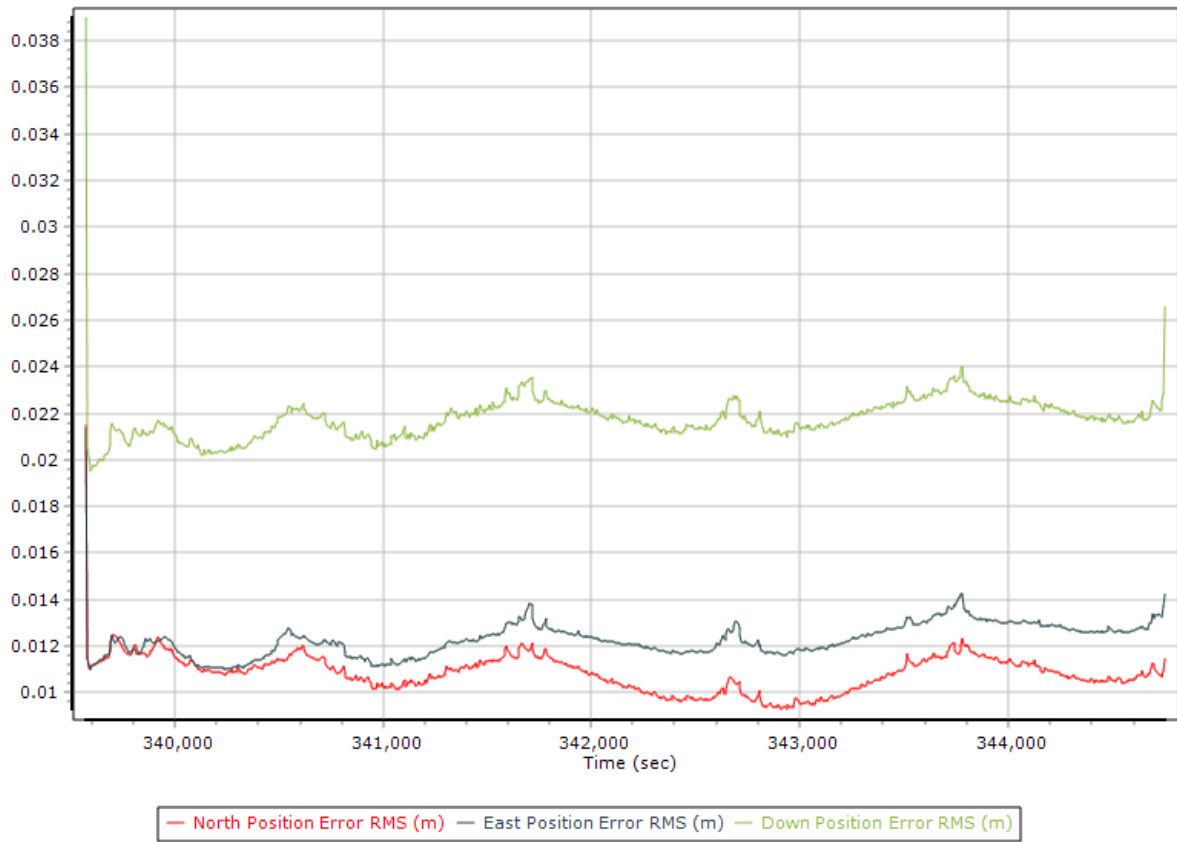
Aircraft to Reference Mounting Angles

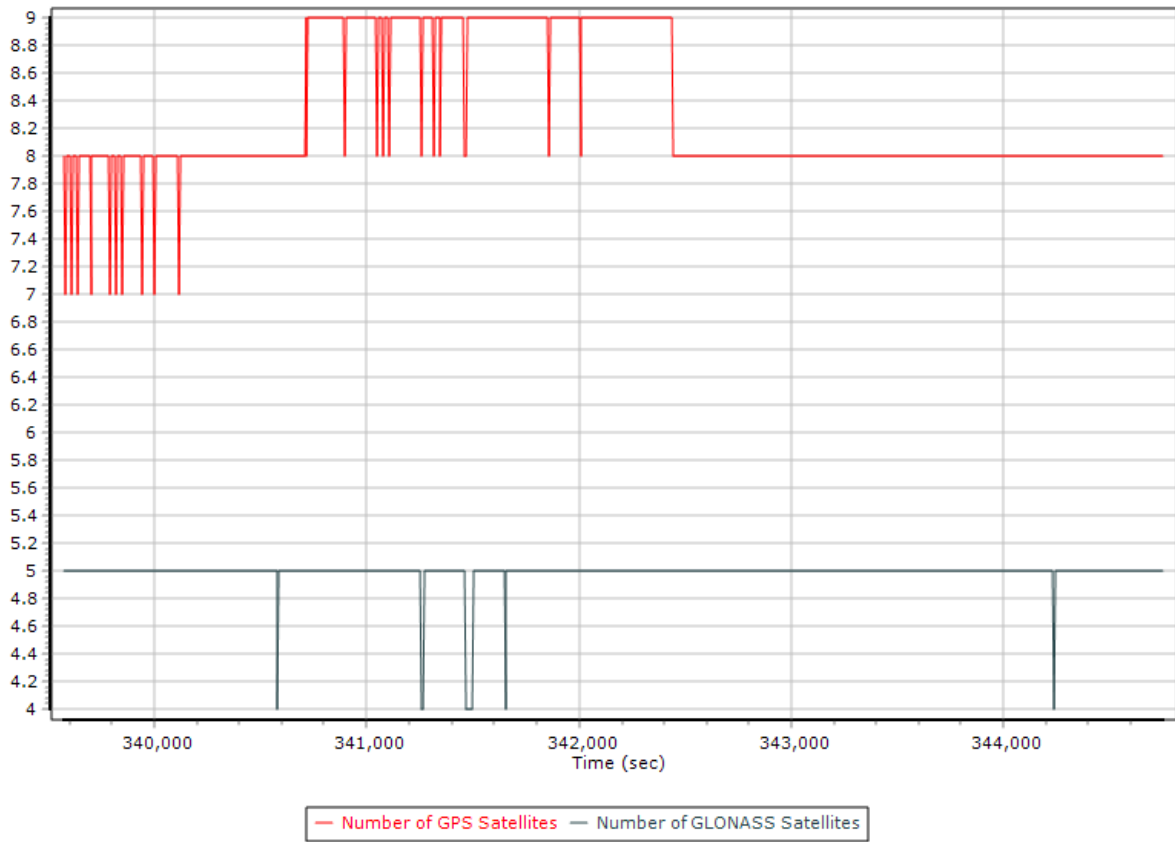
X

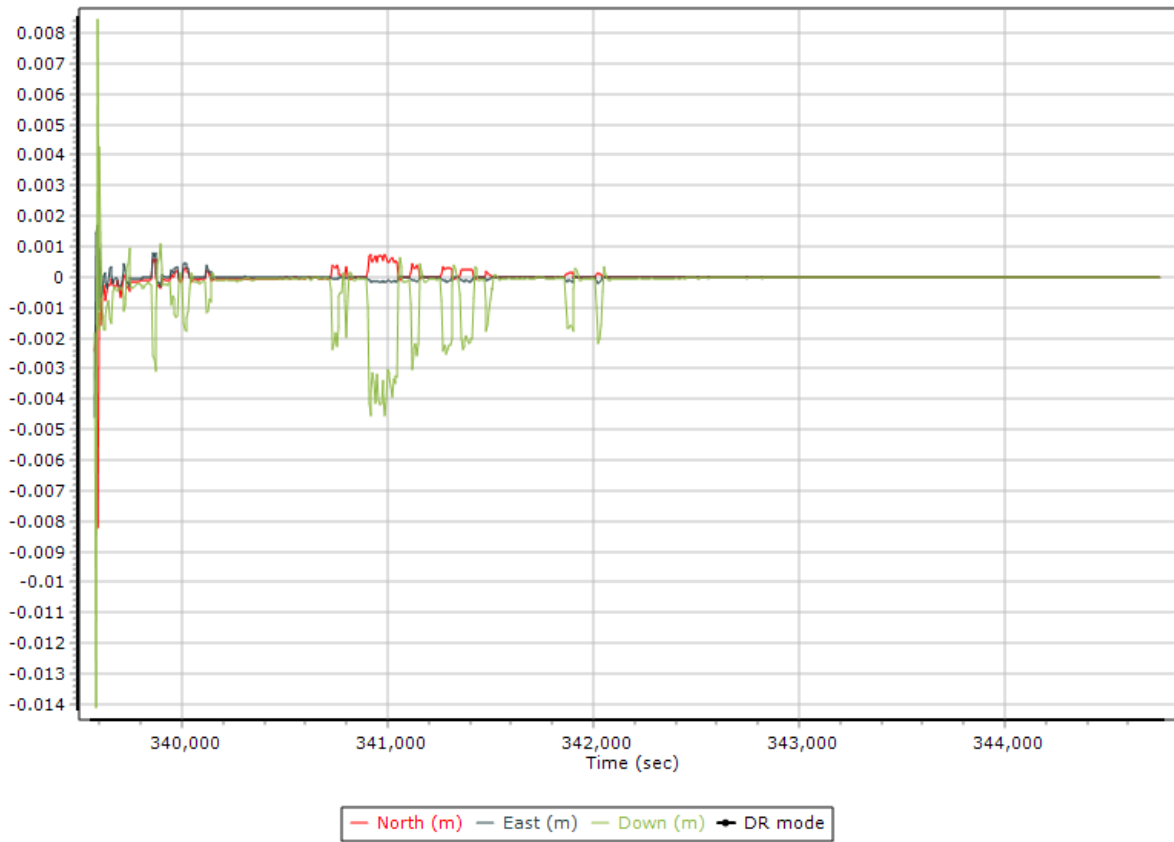
Y

Z









Project Settings [X]

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

Timing

Start: 339568.686
 End: 344759.867

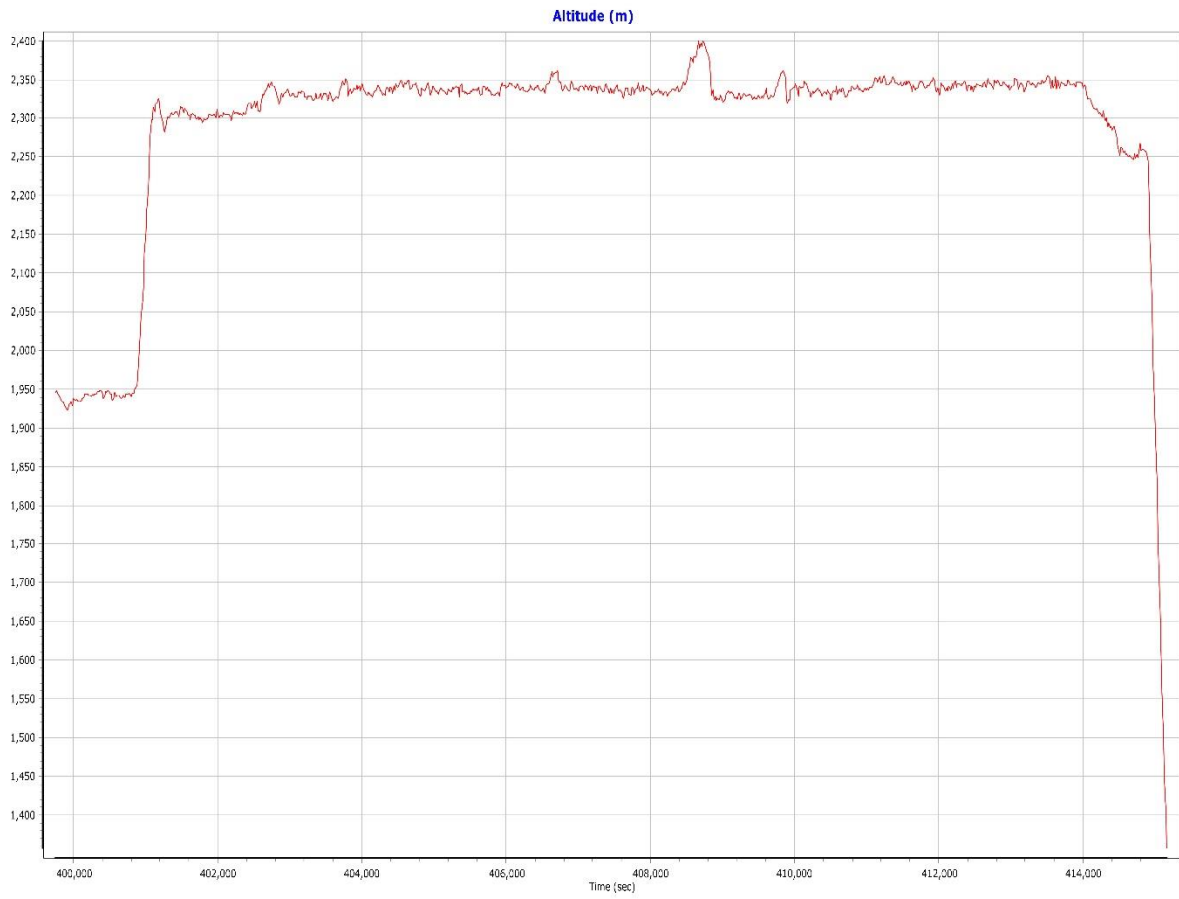
Entire time interval
 Seconds of start week

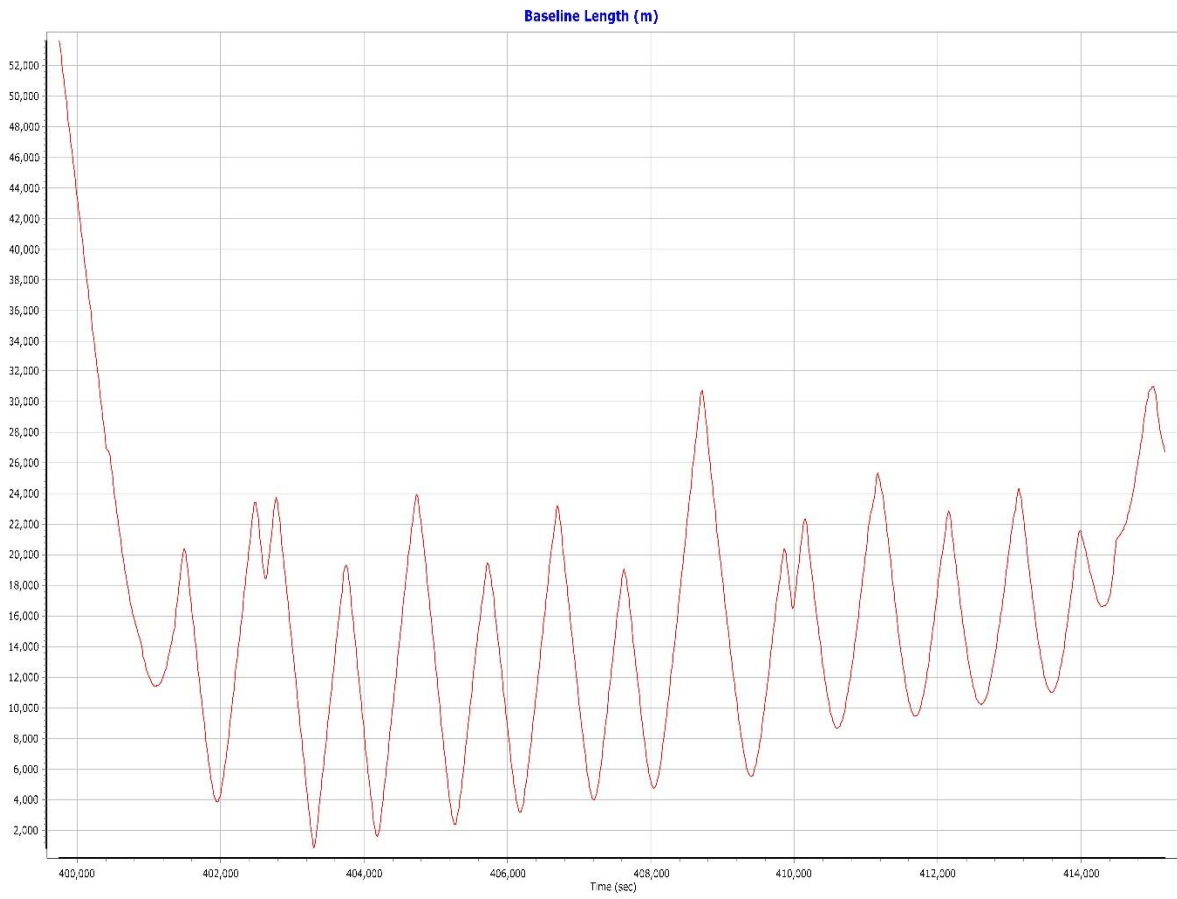
UTC Offset: 18.000

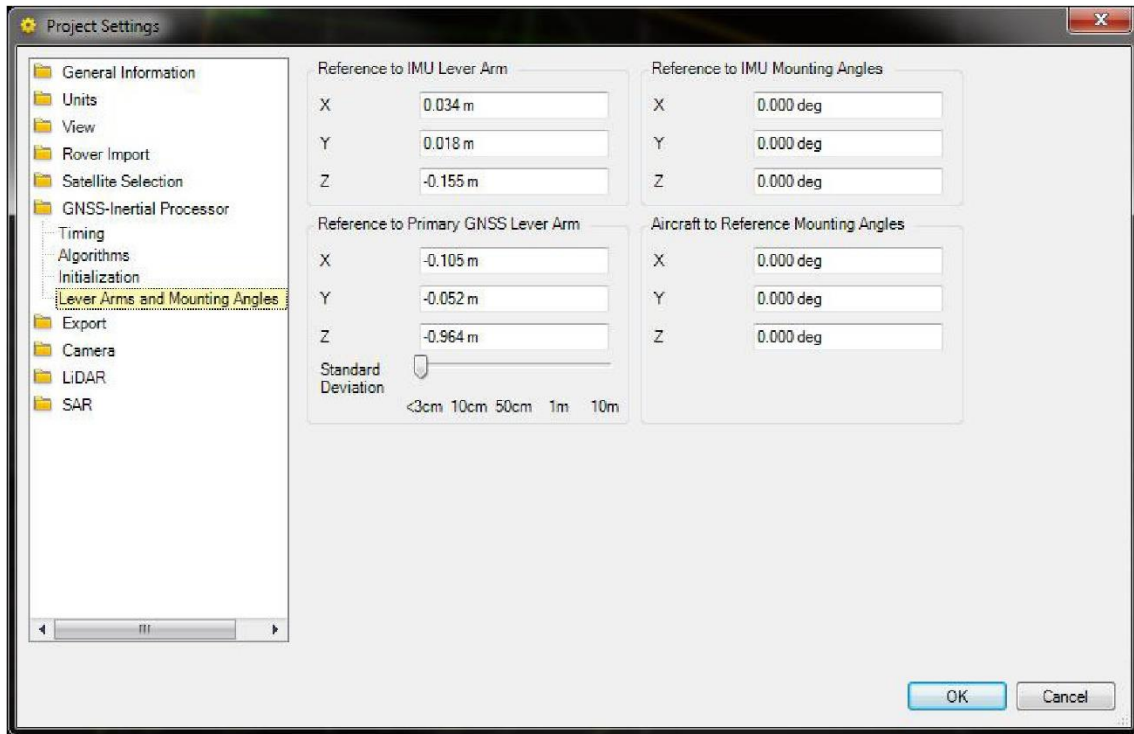
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

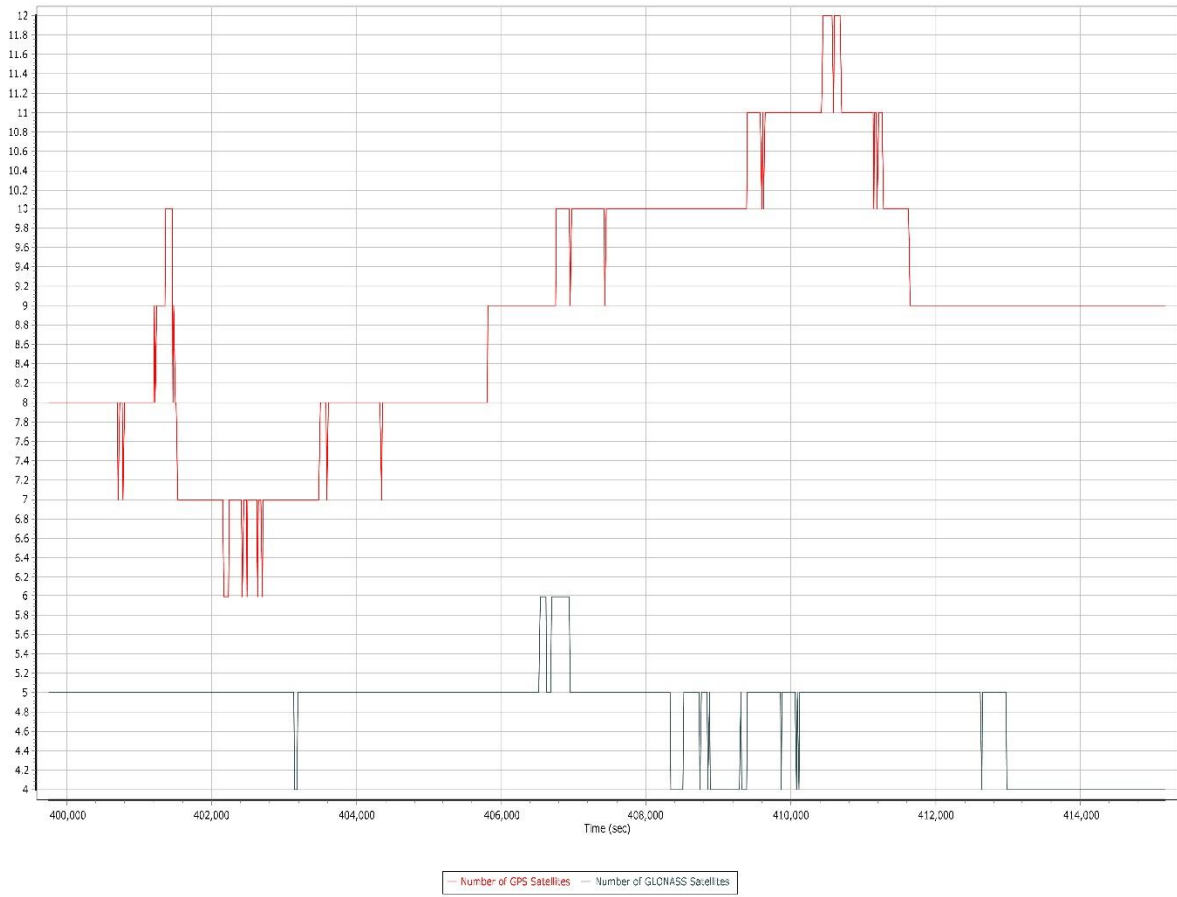
OK Cancel

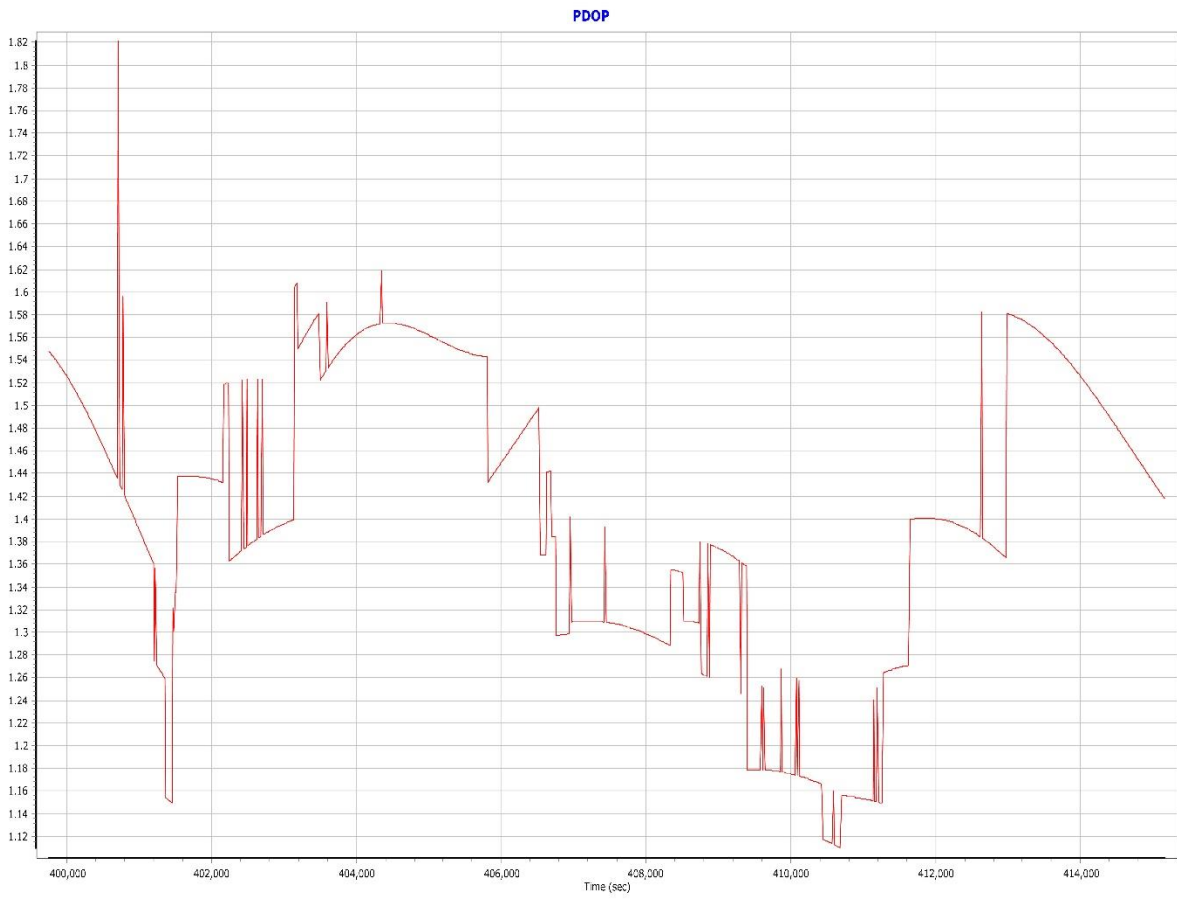
UNB18039A

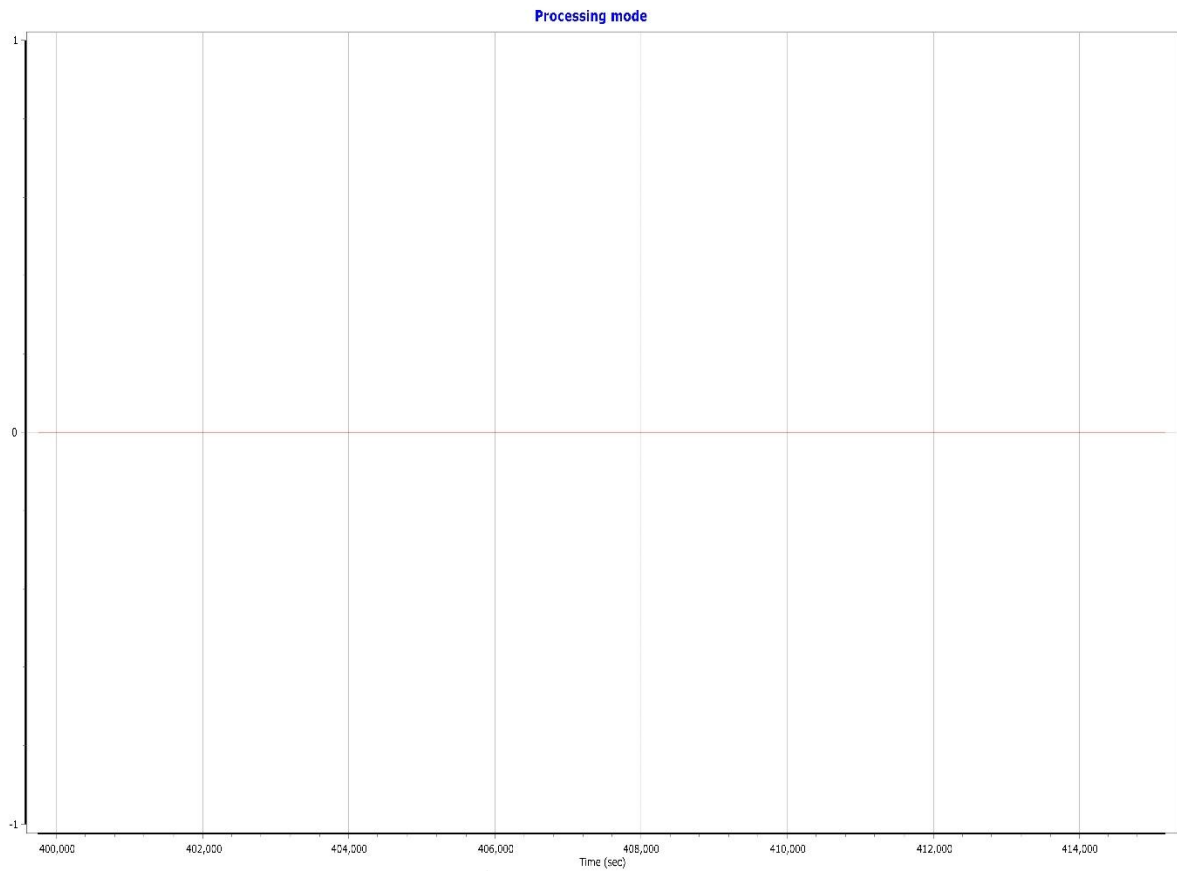






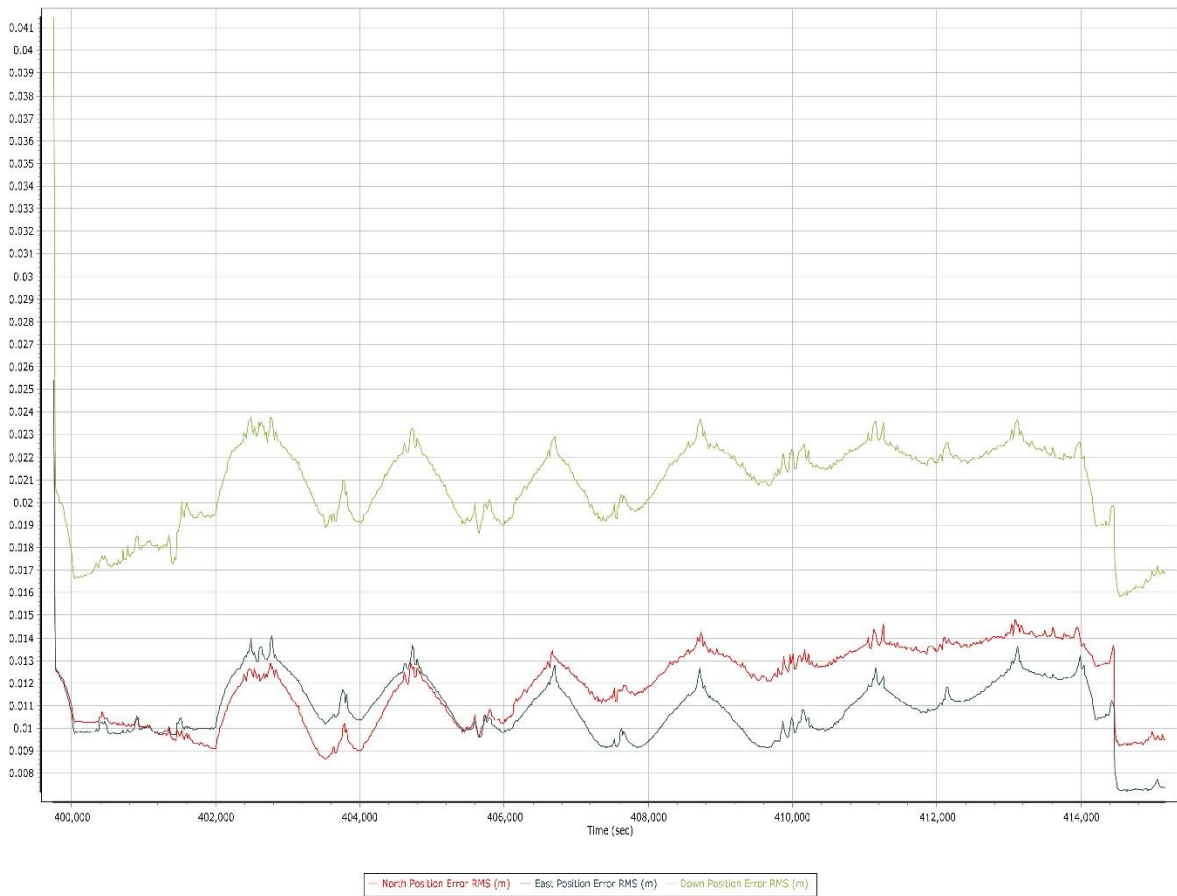


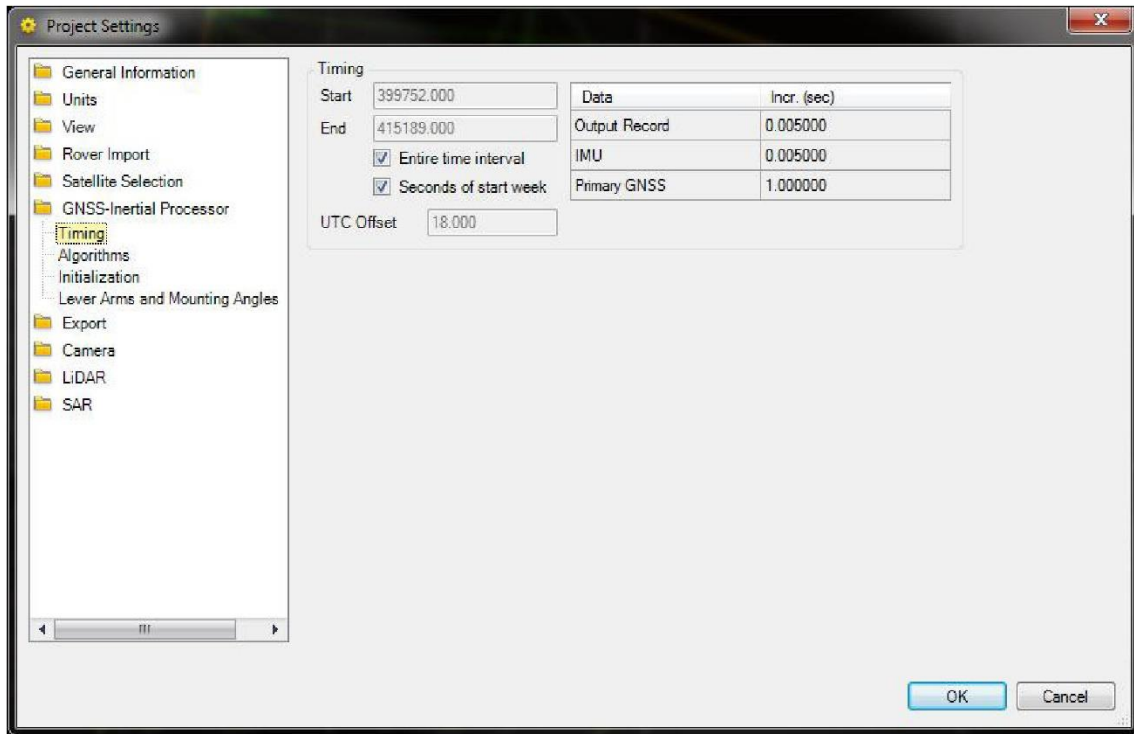


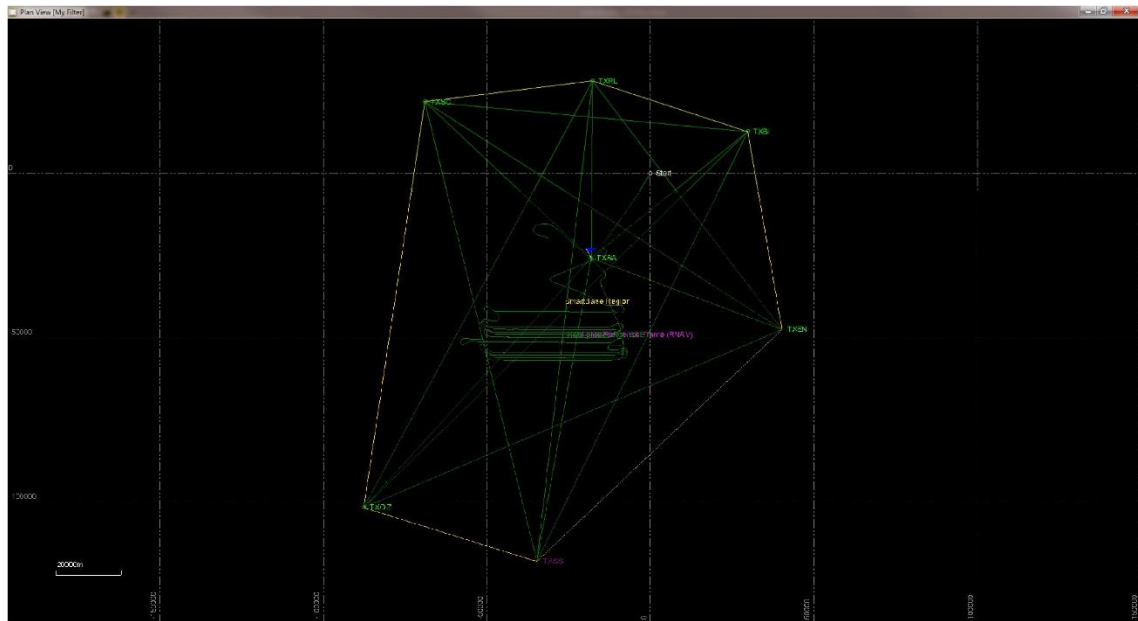


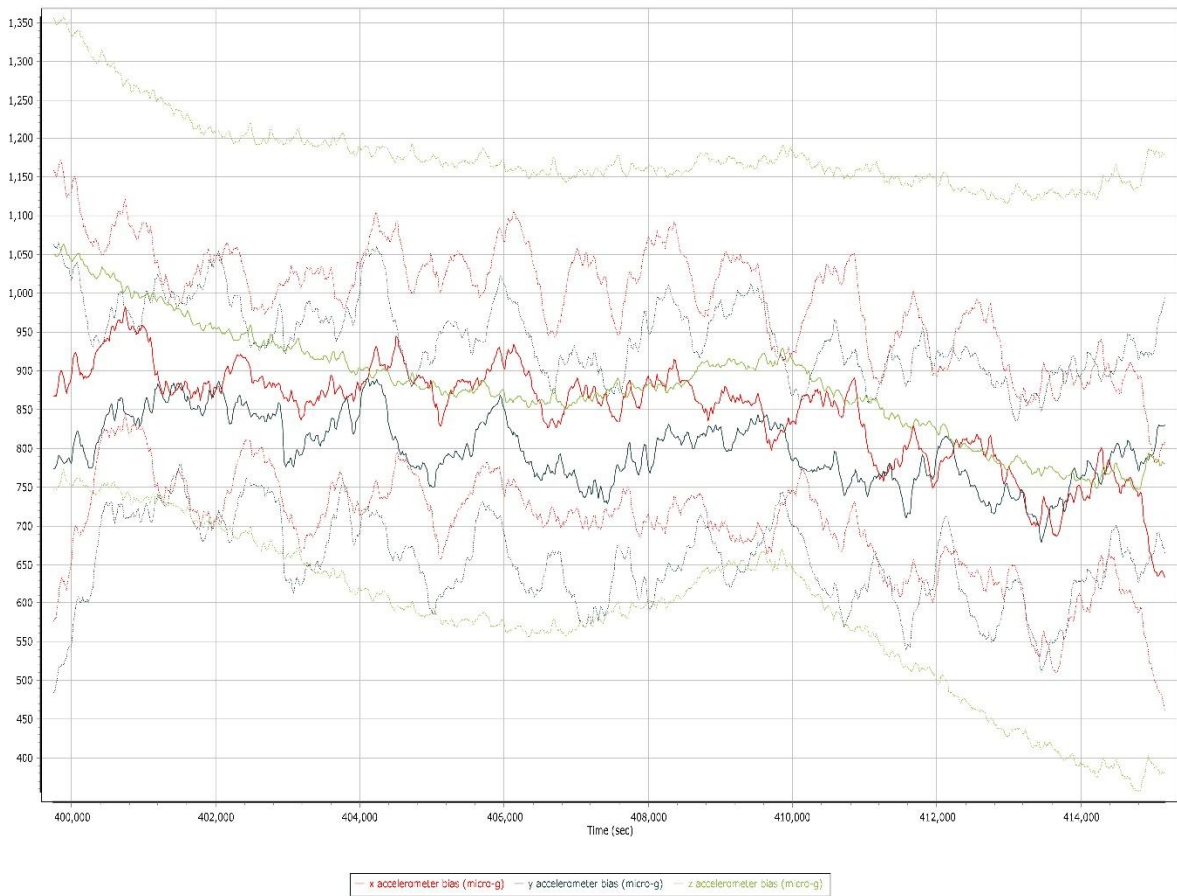
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IA*PPF, 6 = C/A, 7 = GNSS Nav, 8 = DR

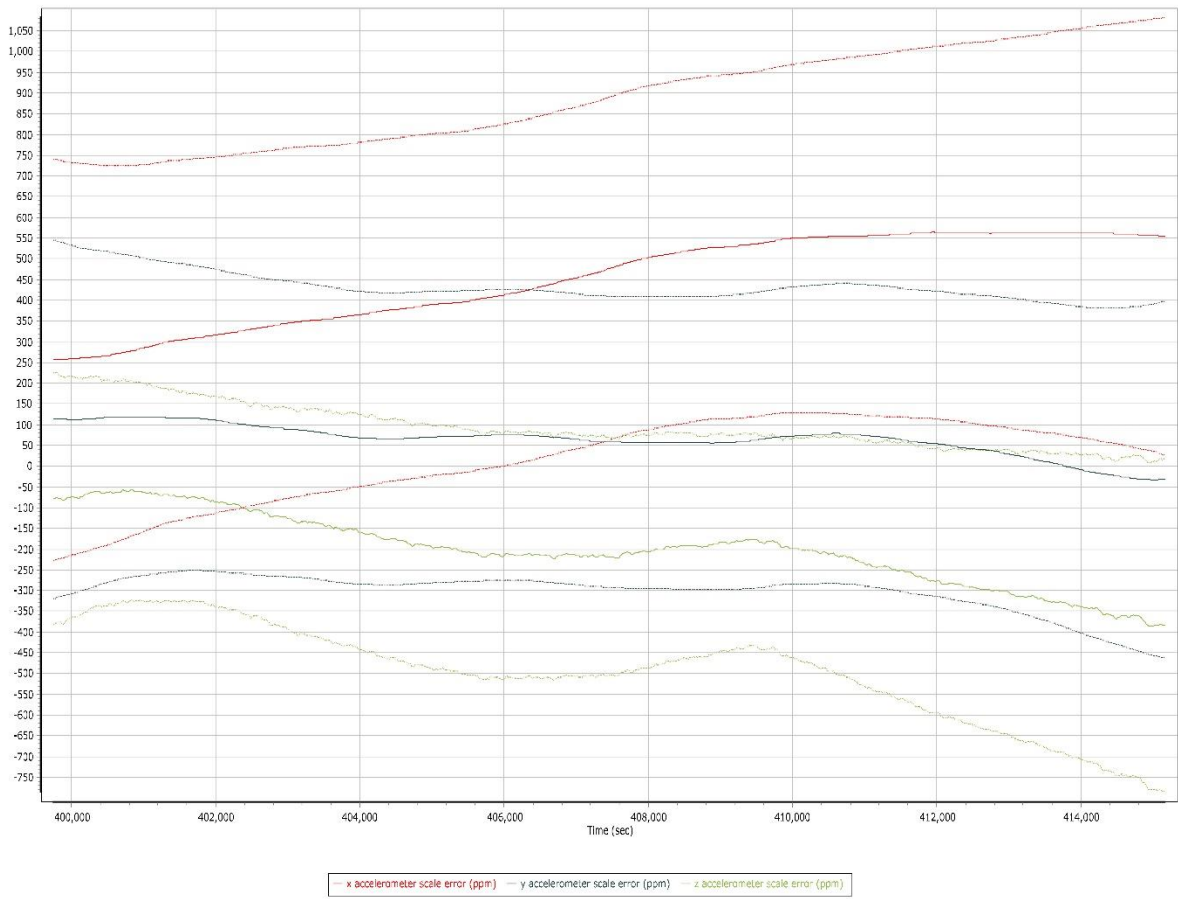


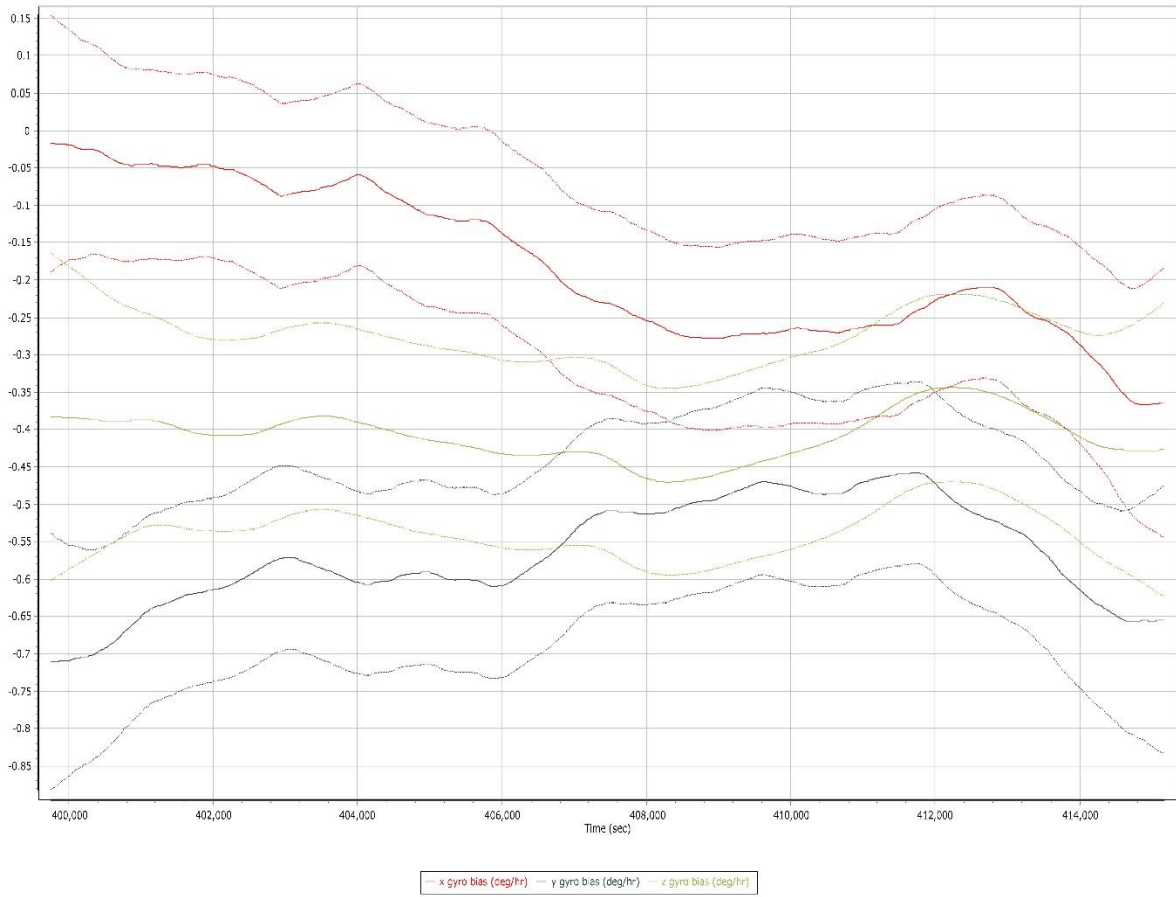


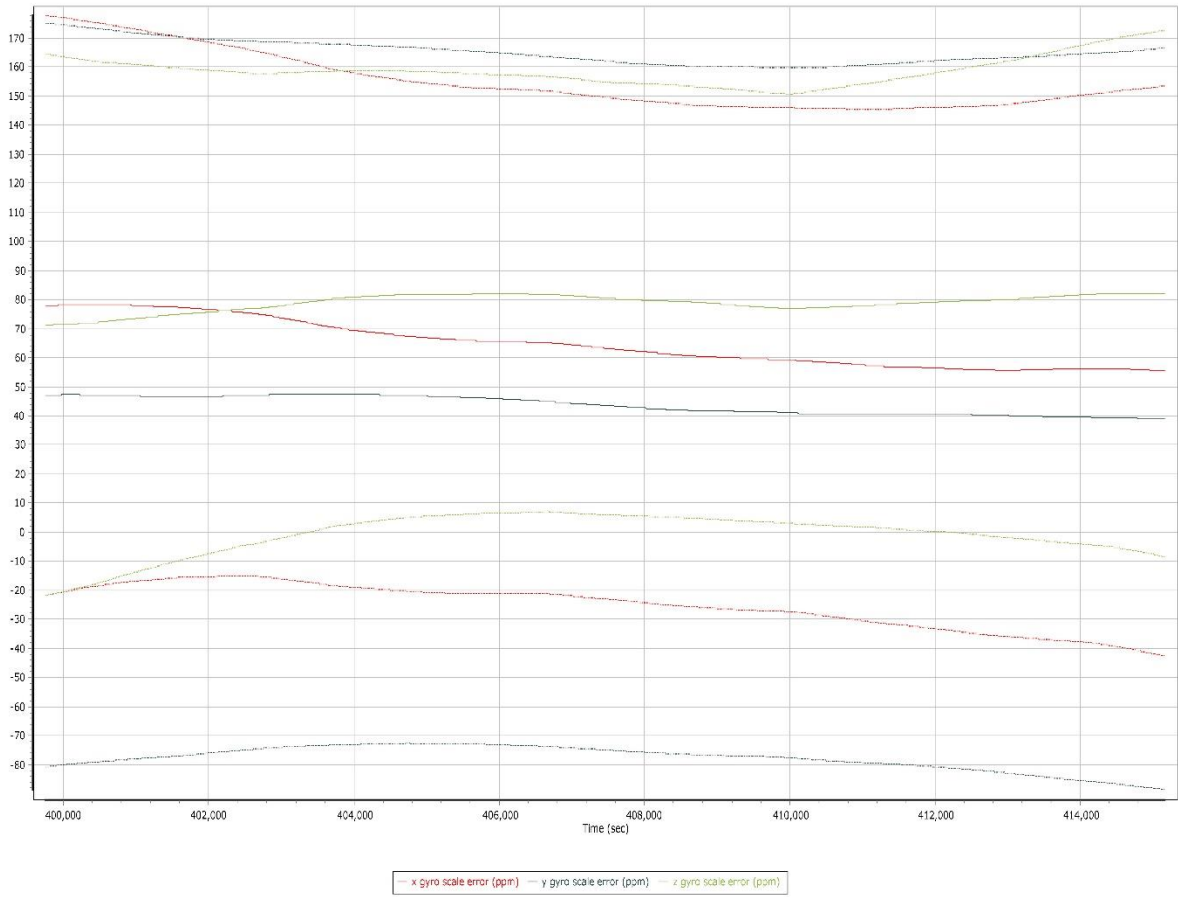




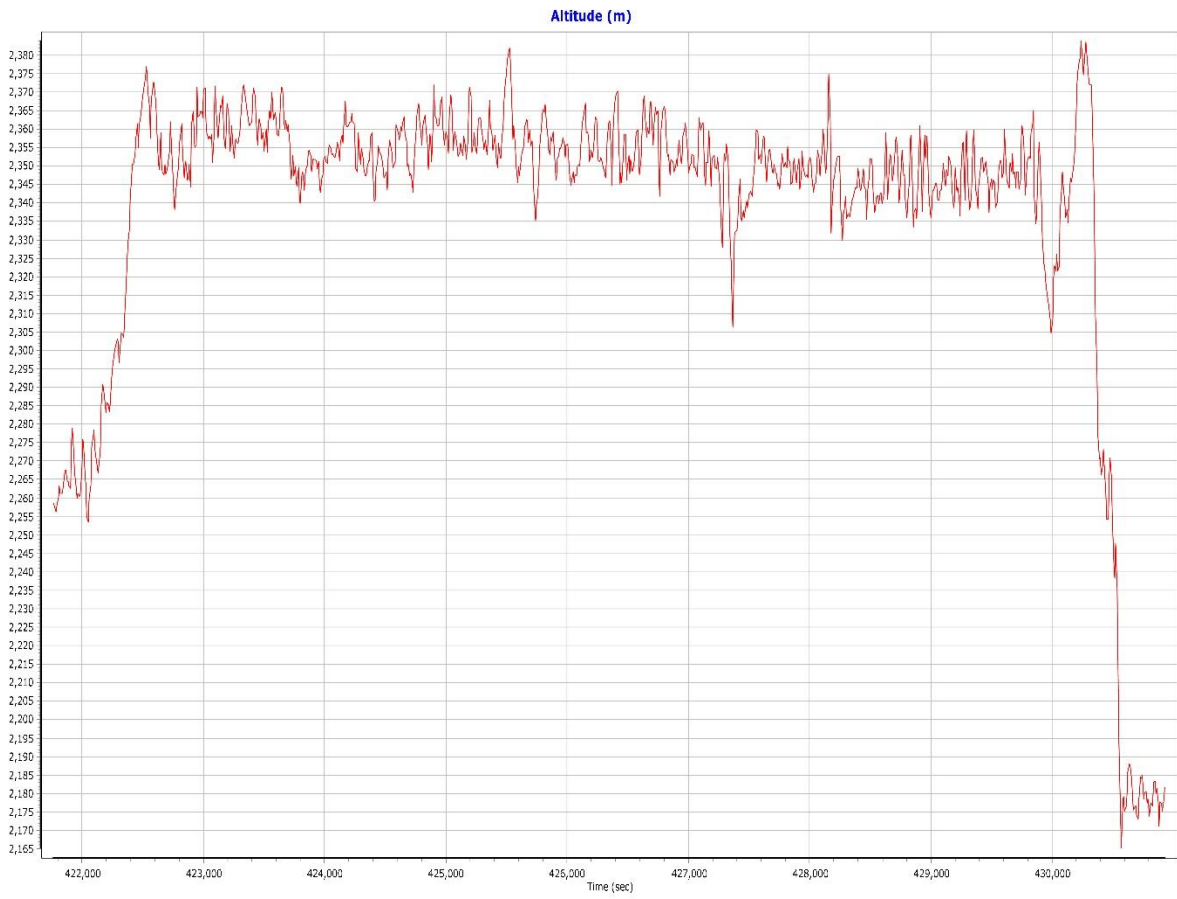


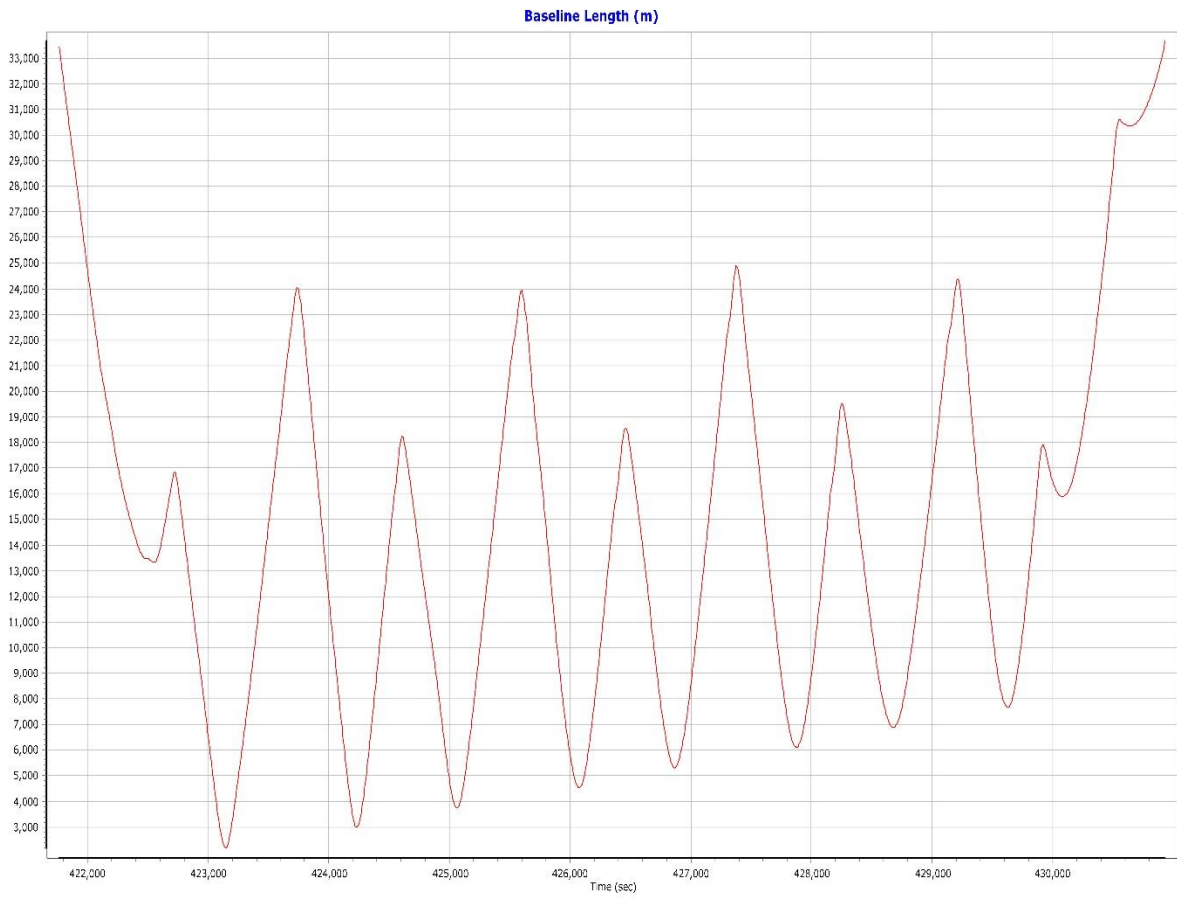


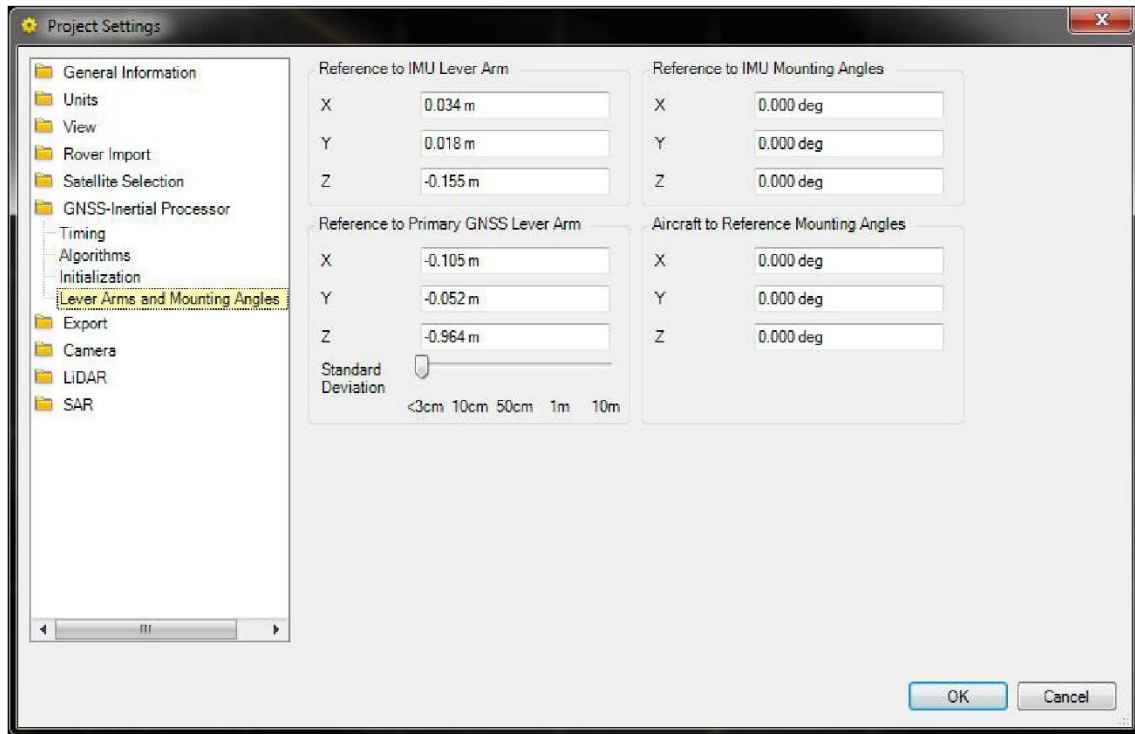


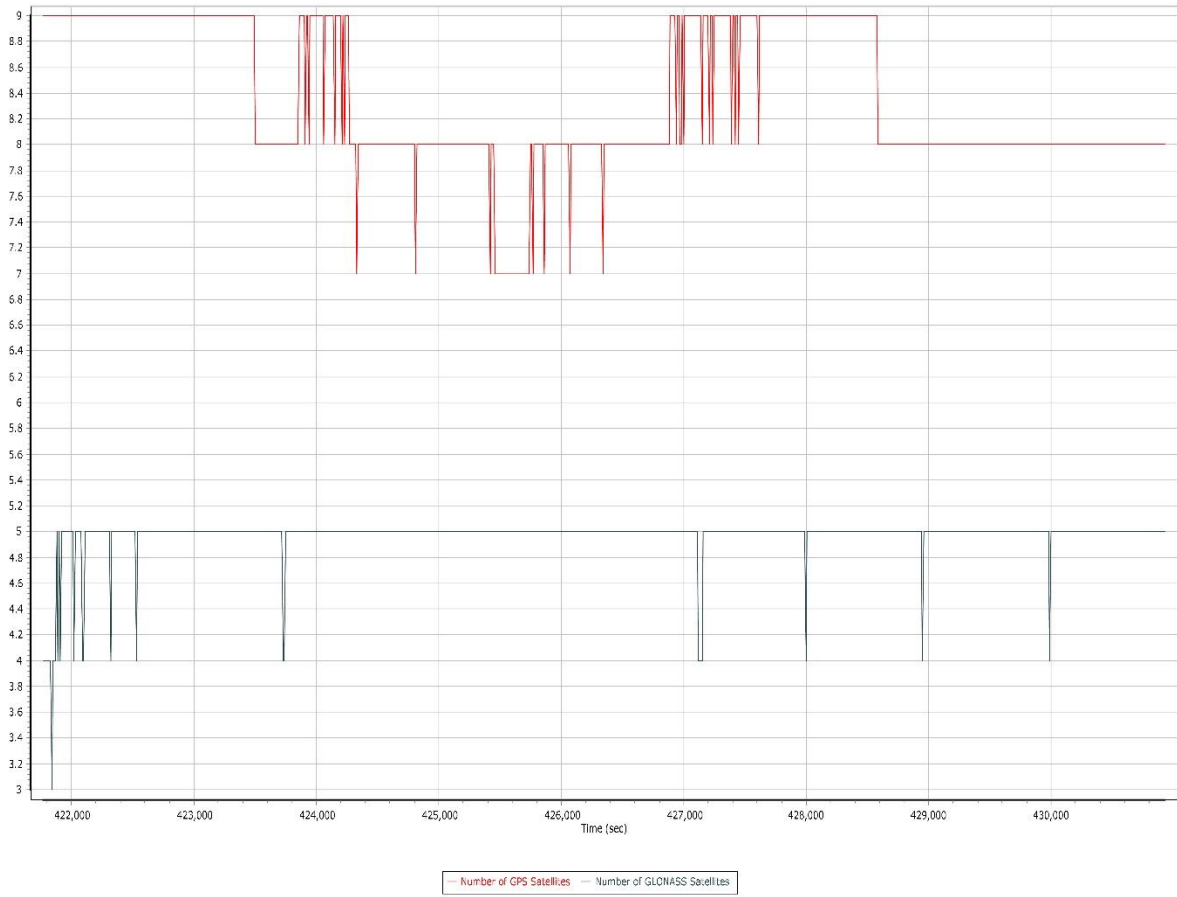


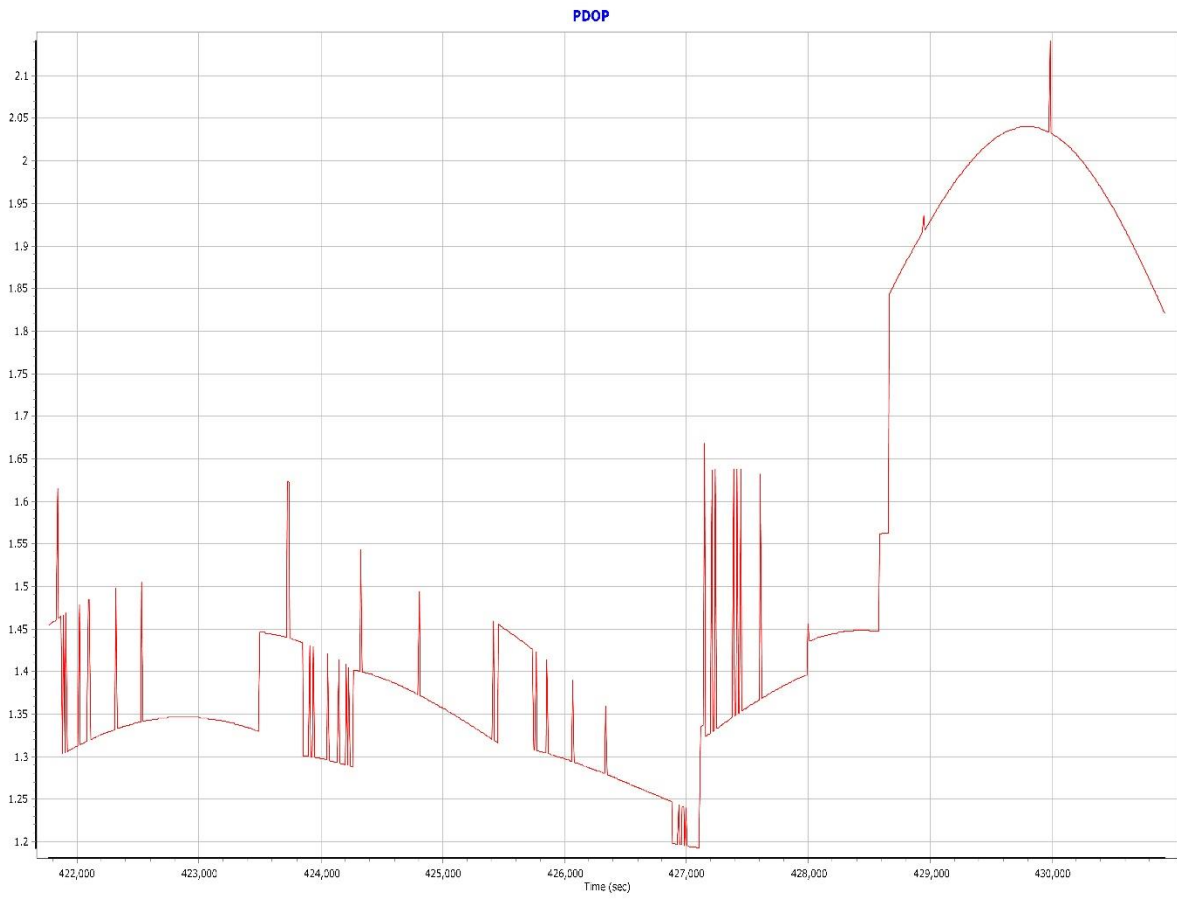
UNB18039B

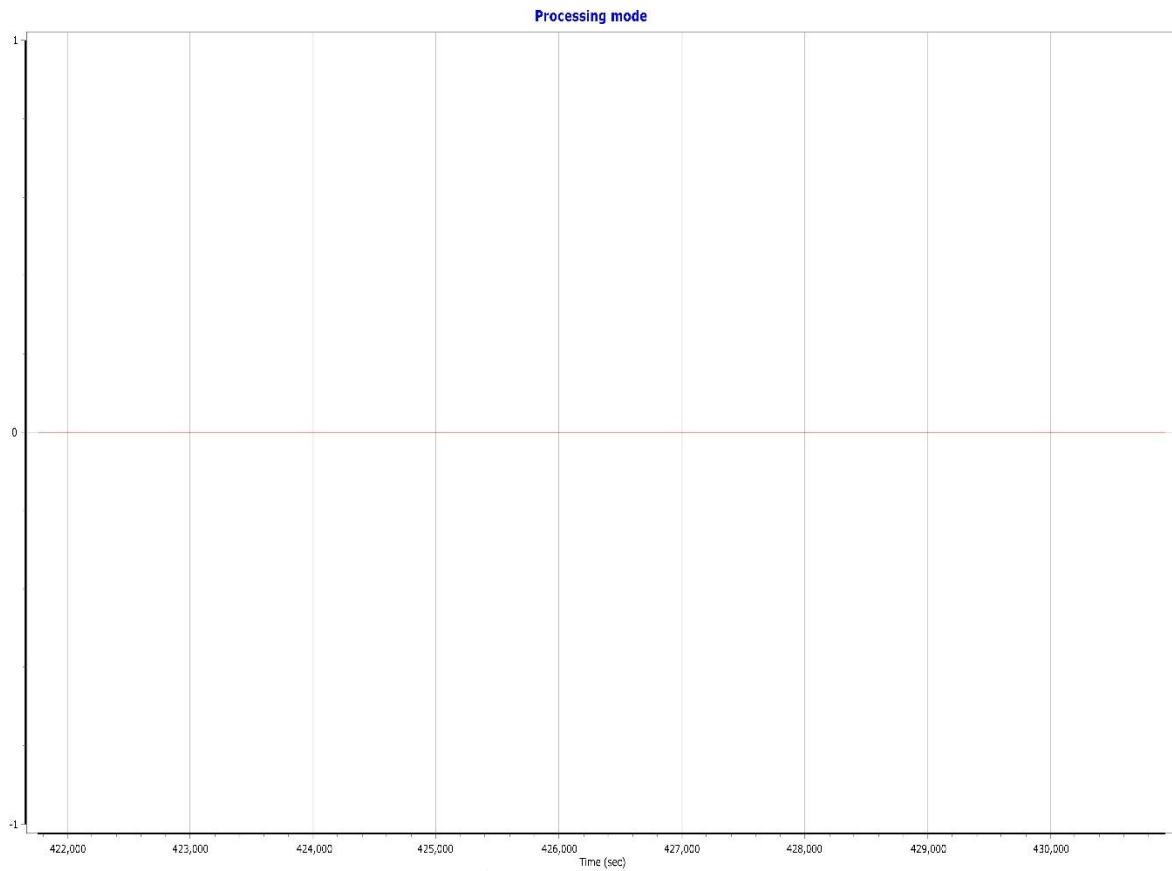








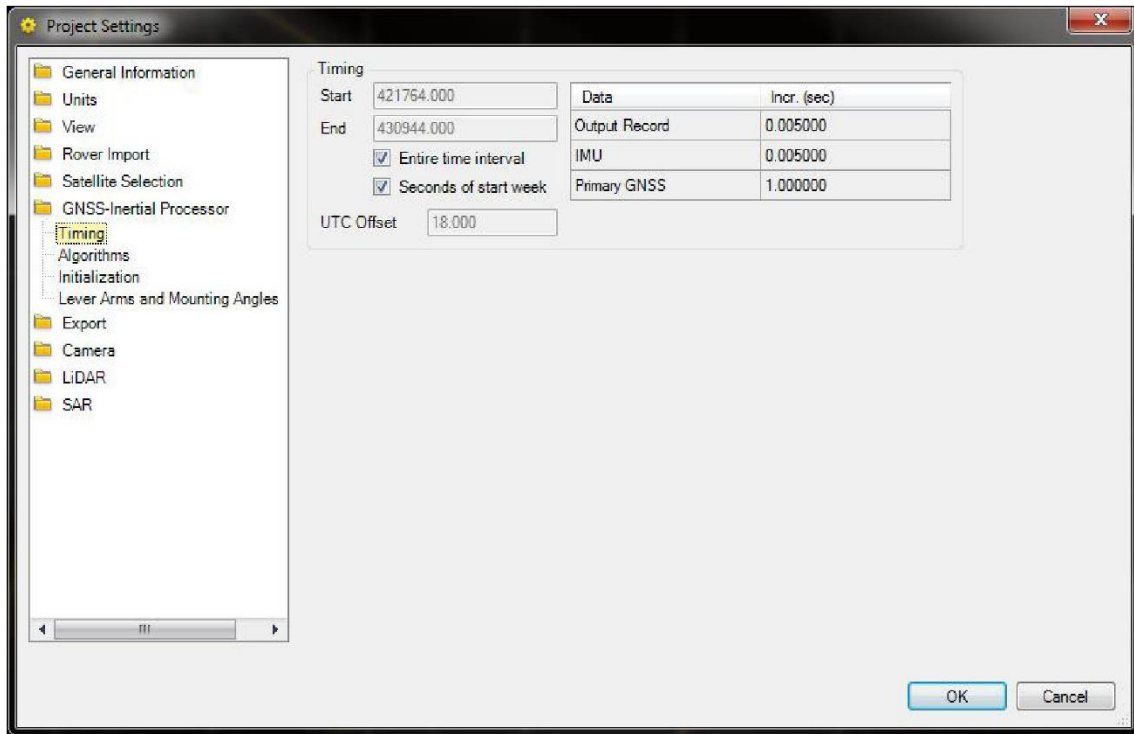


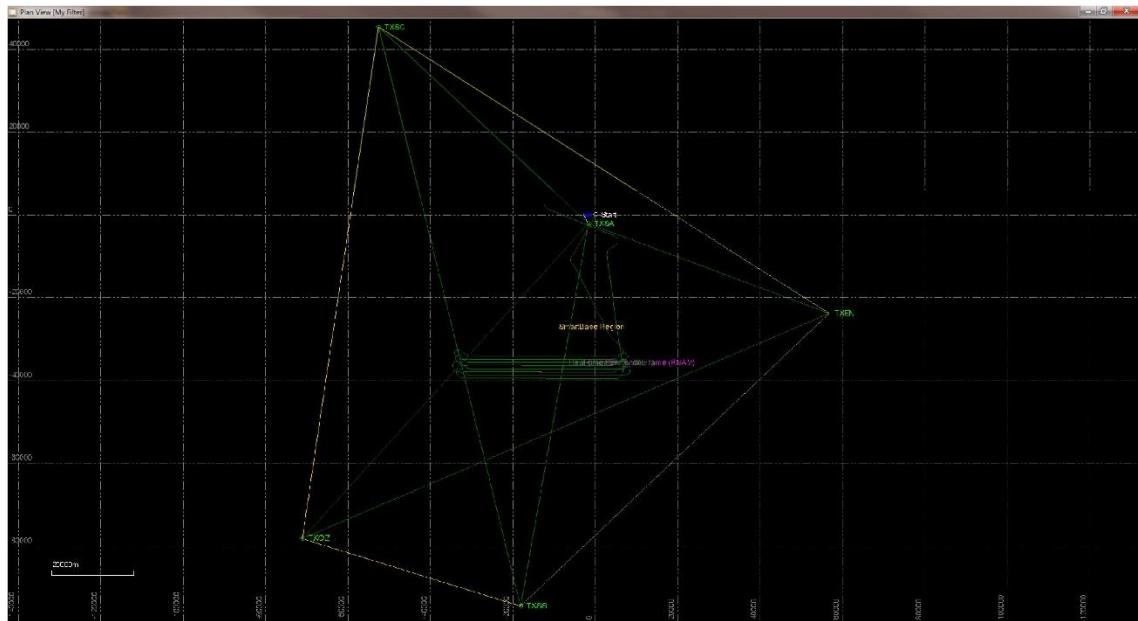


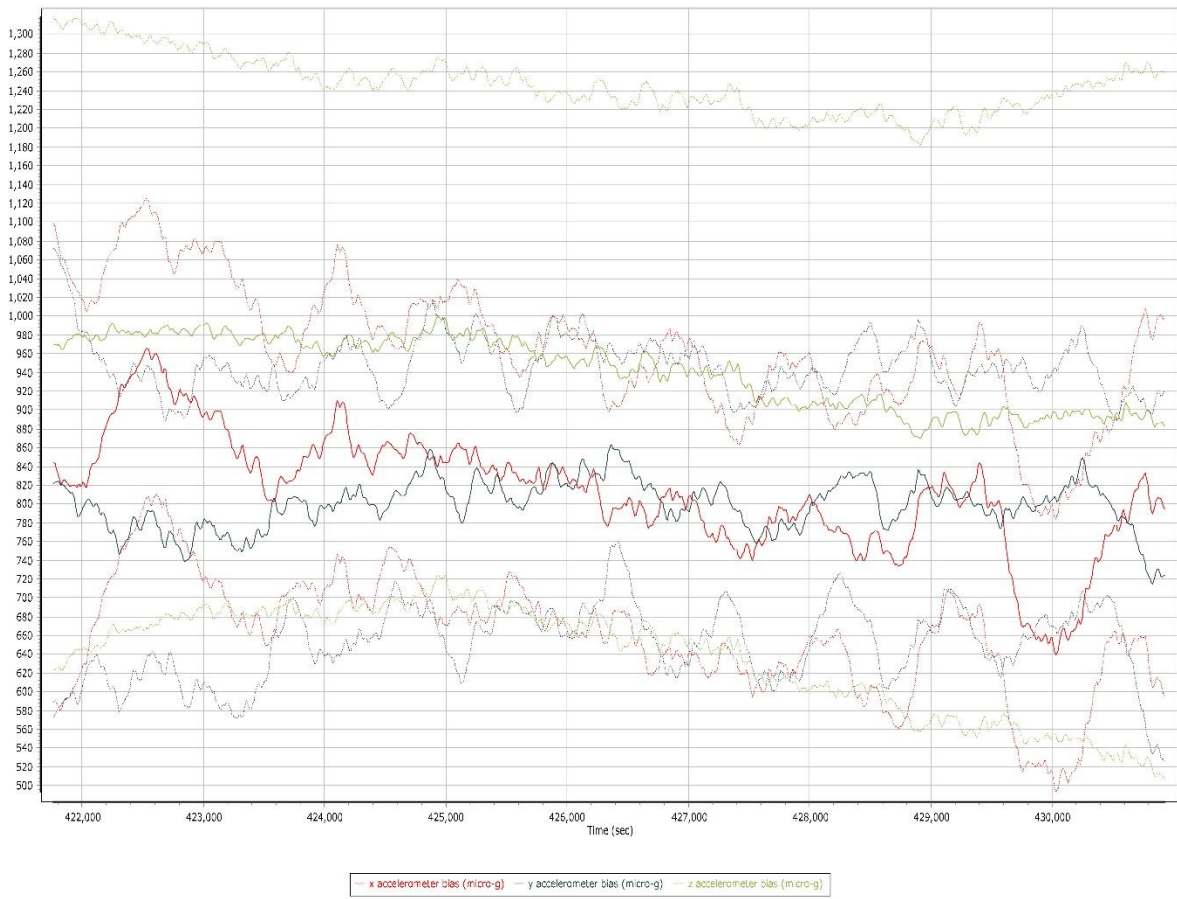
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IA PPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

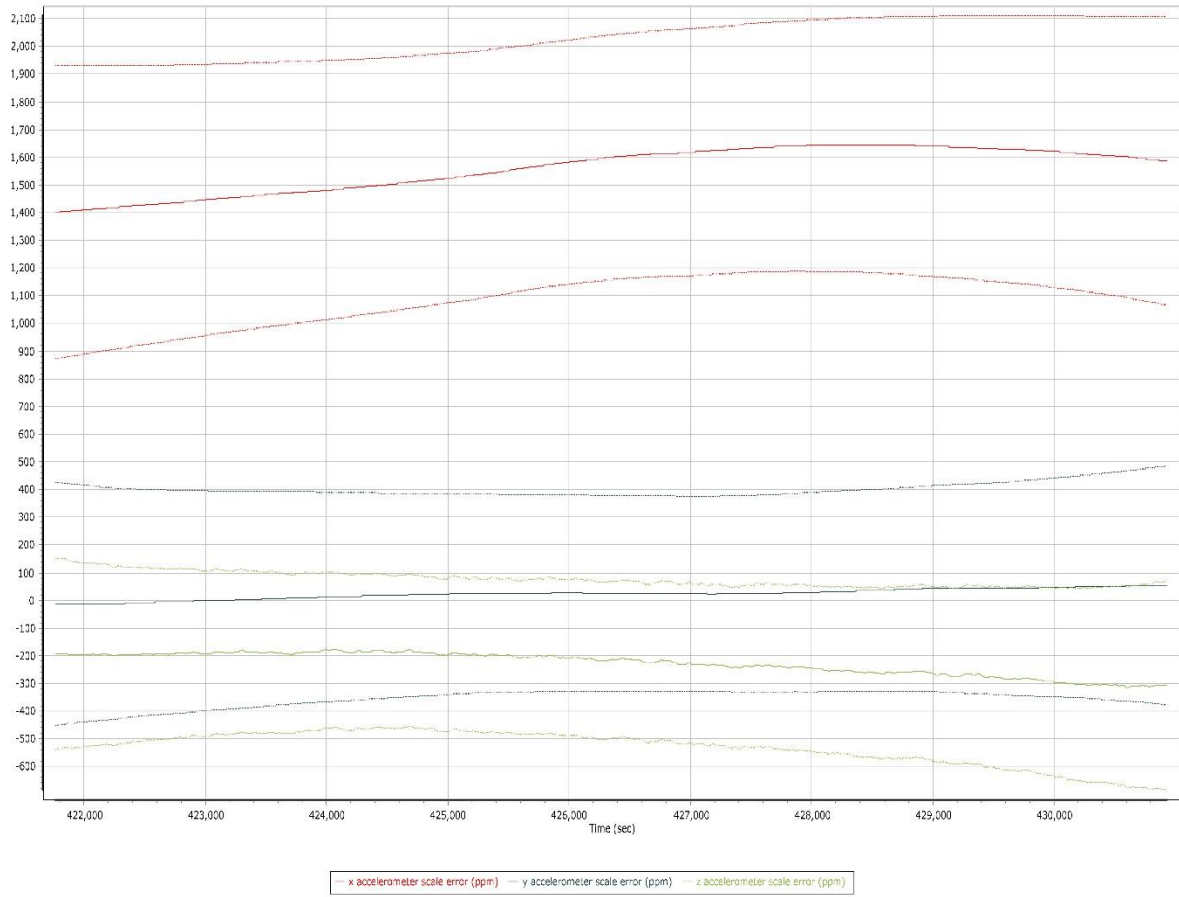


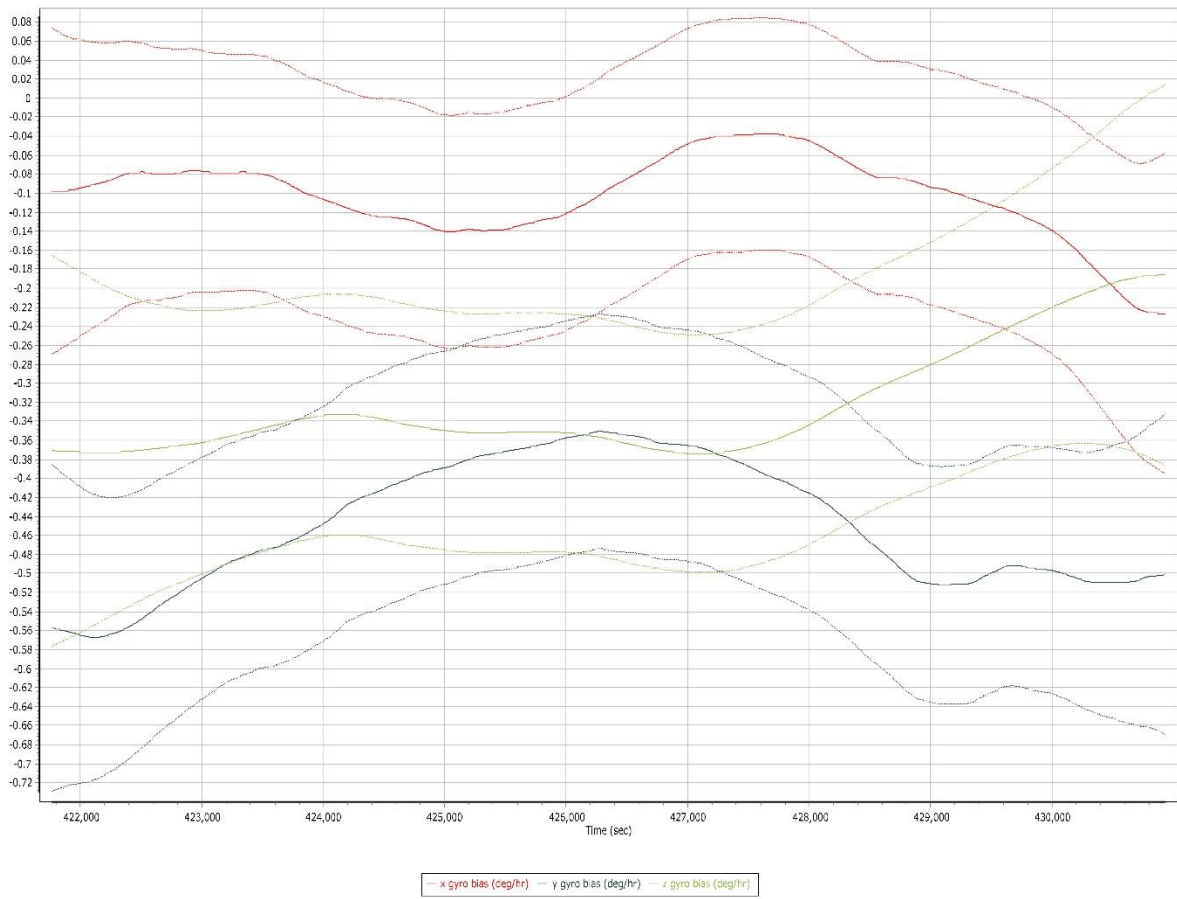


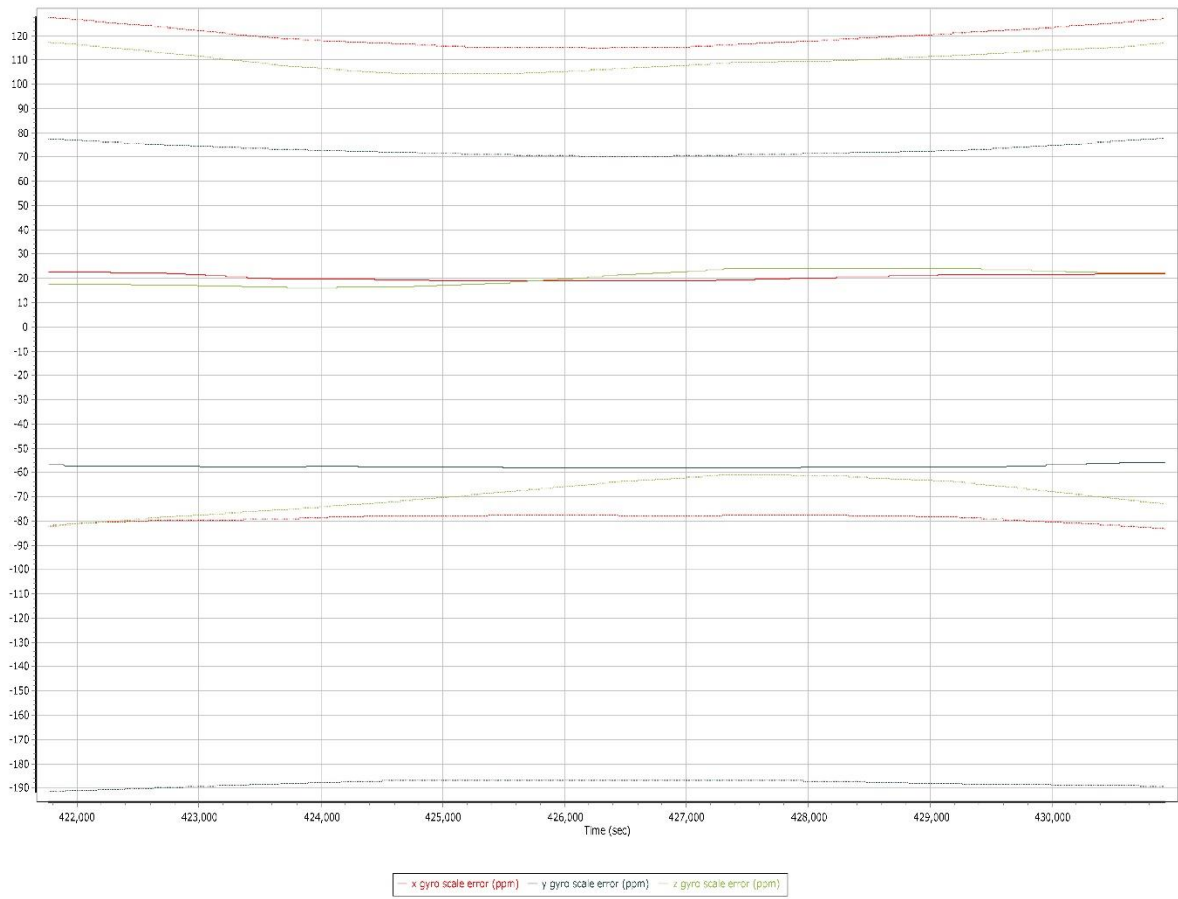




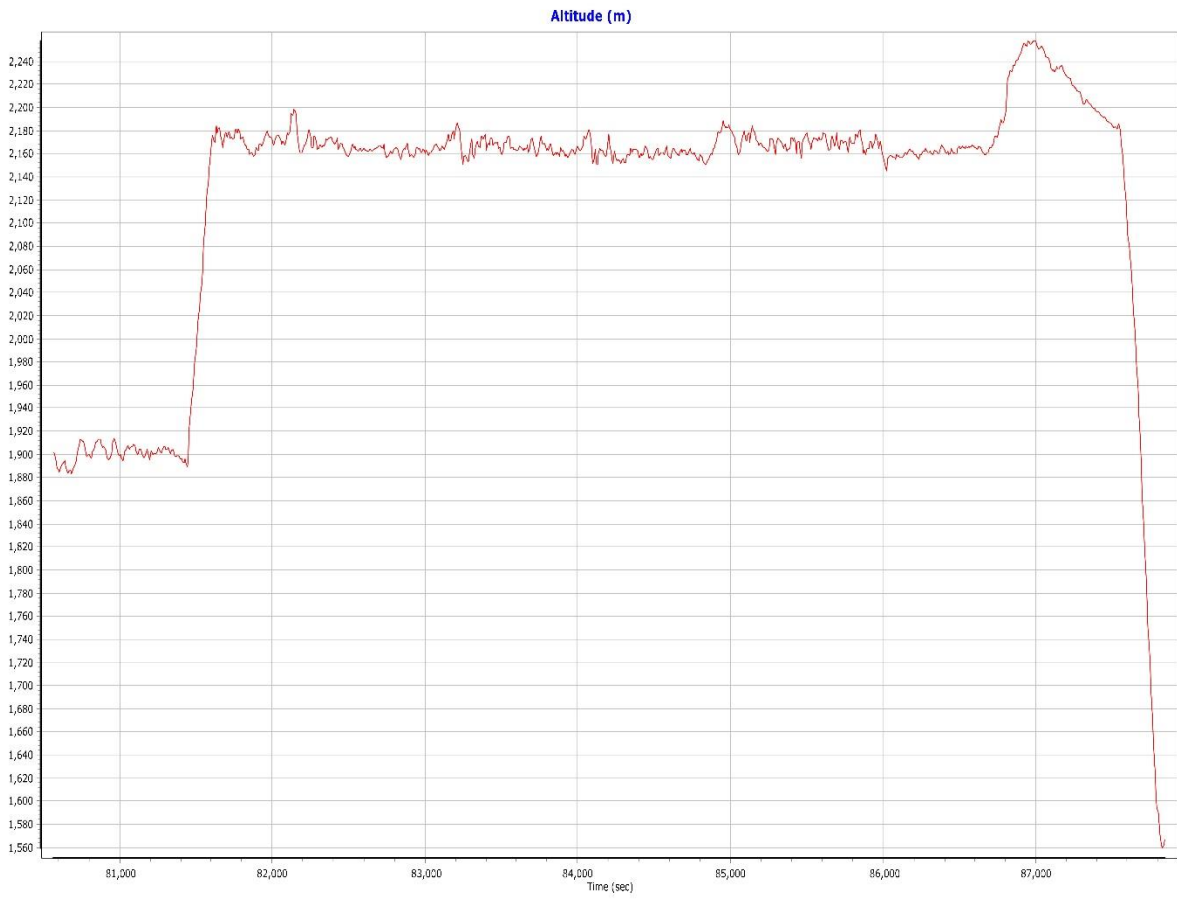


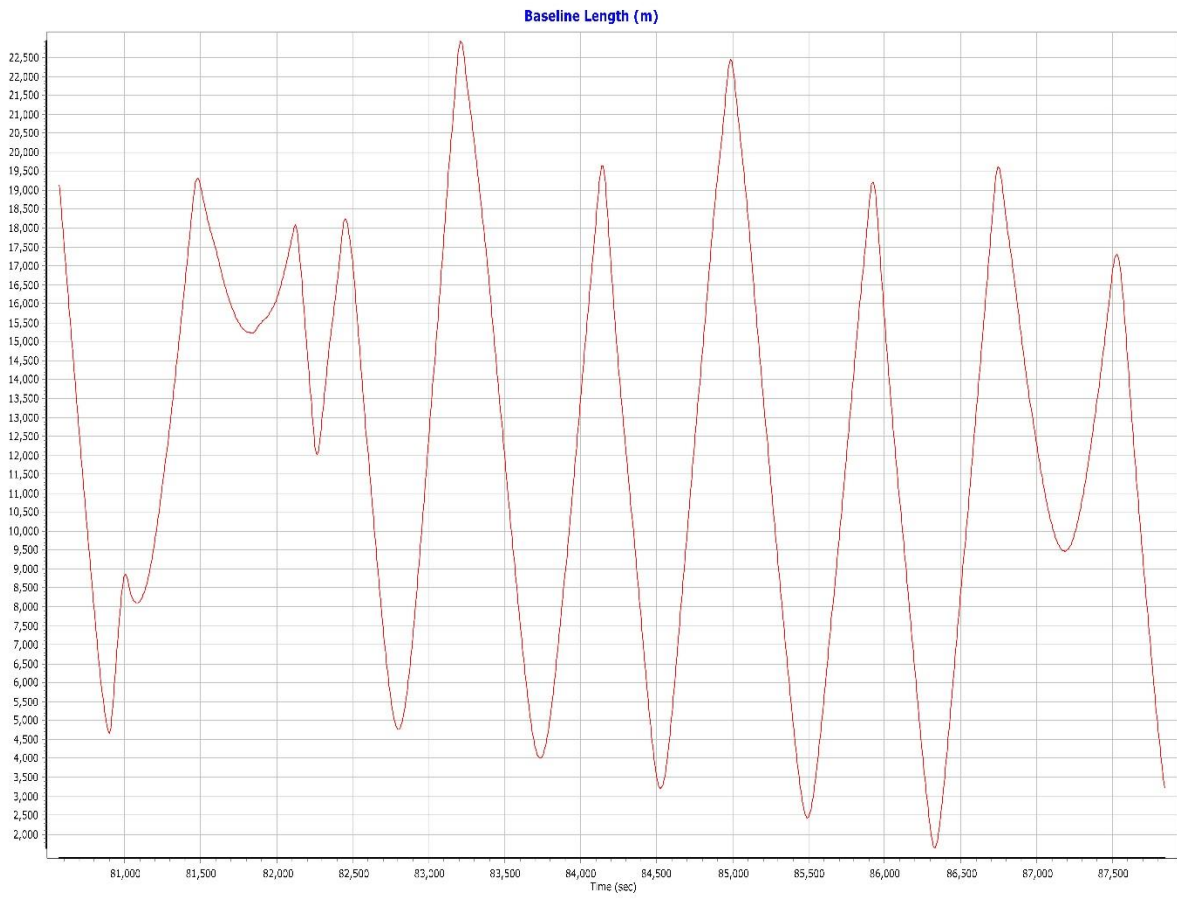


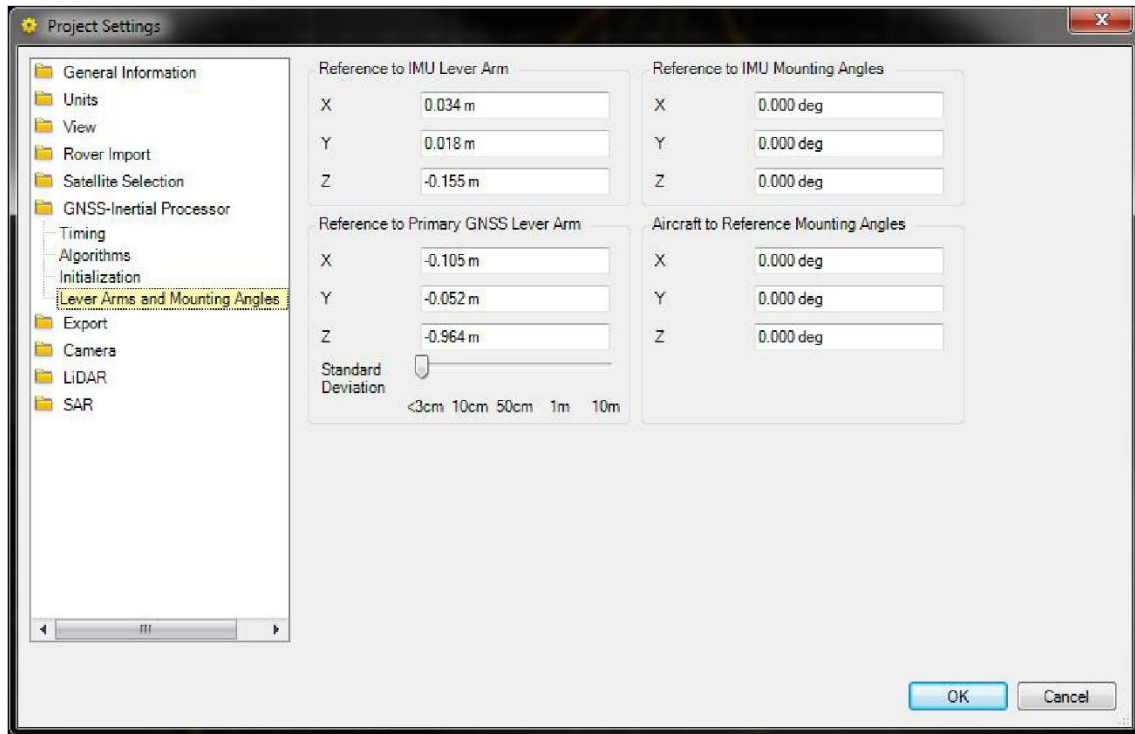


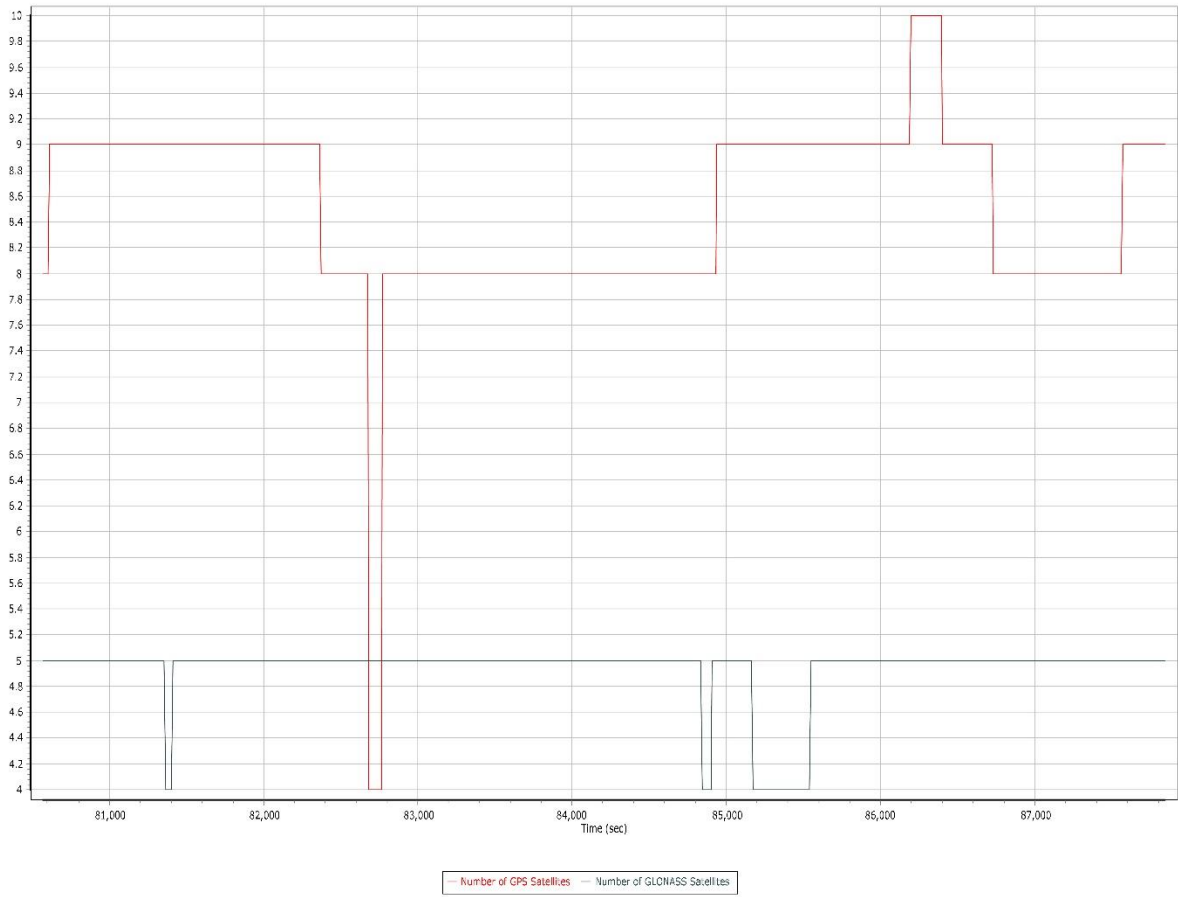


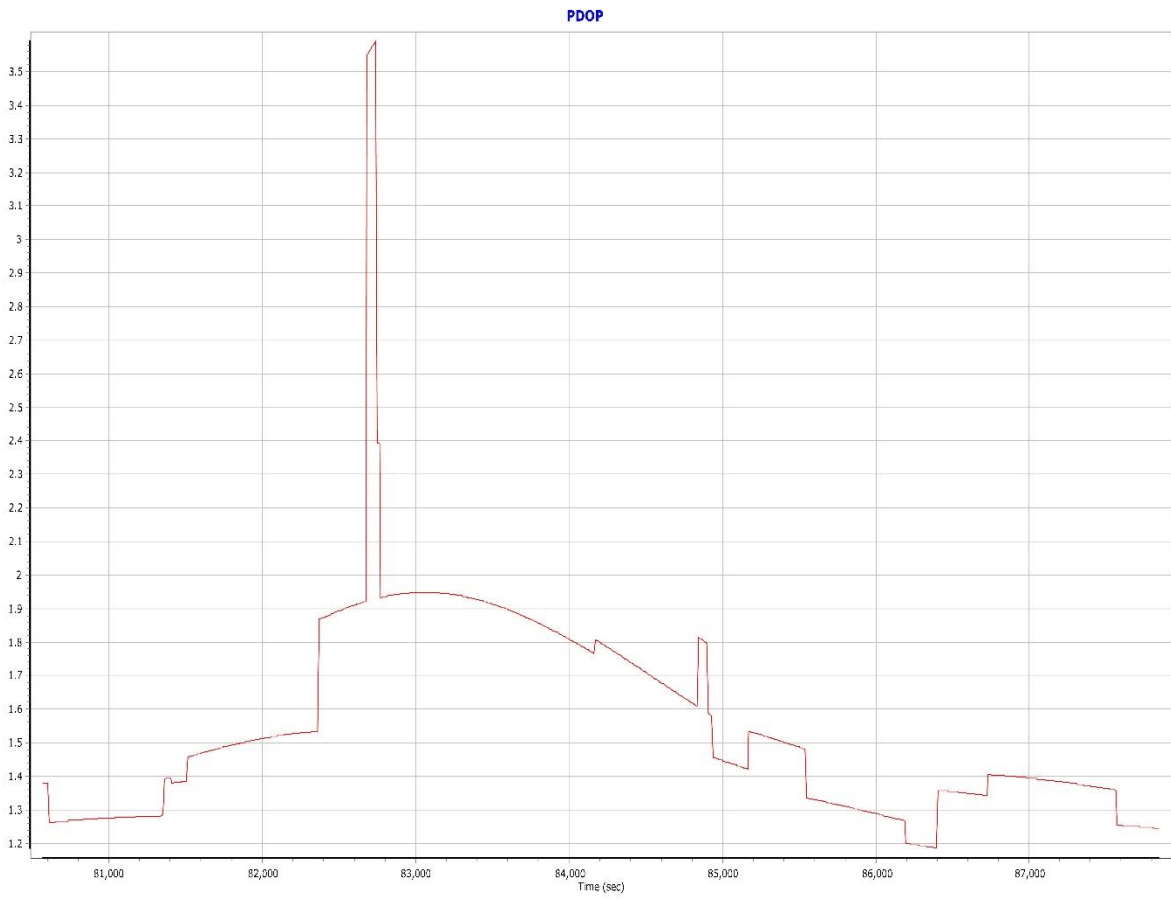
UNB18042A

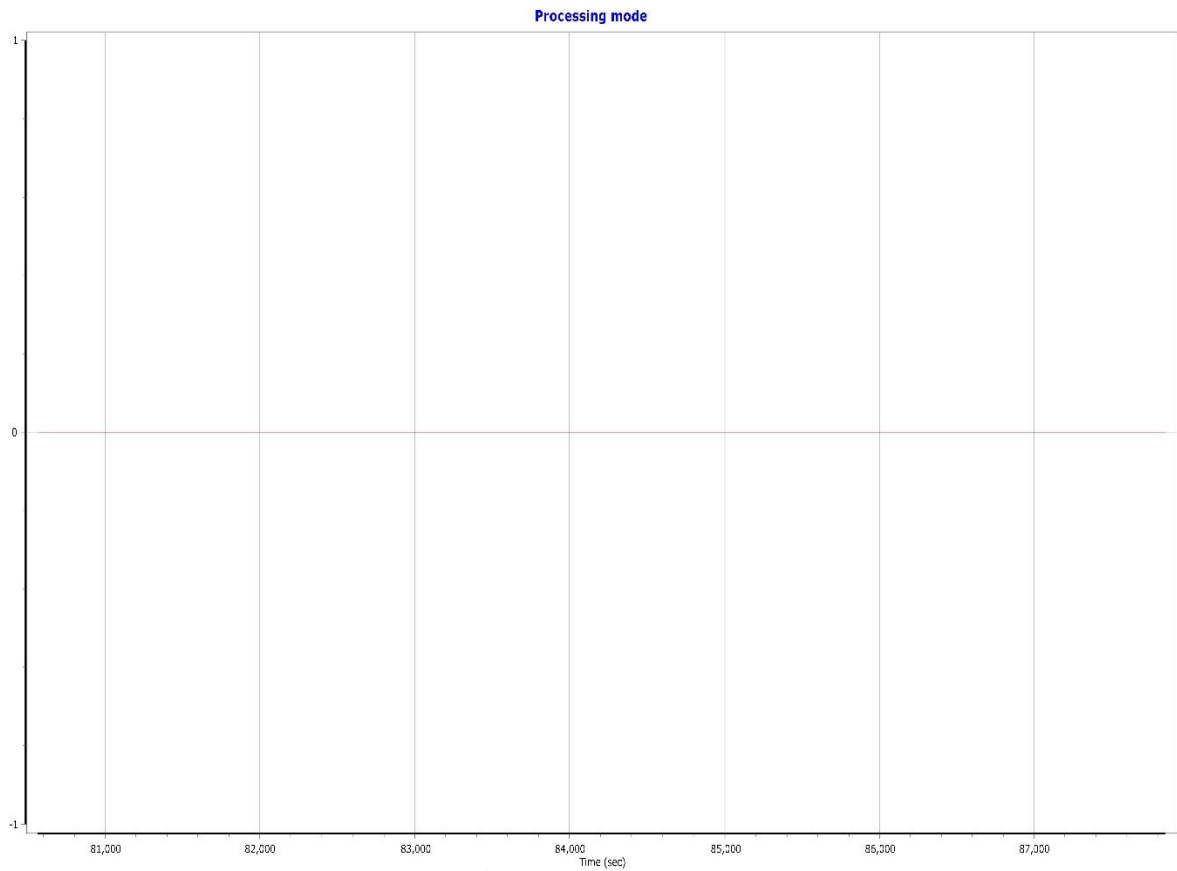




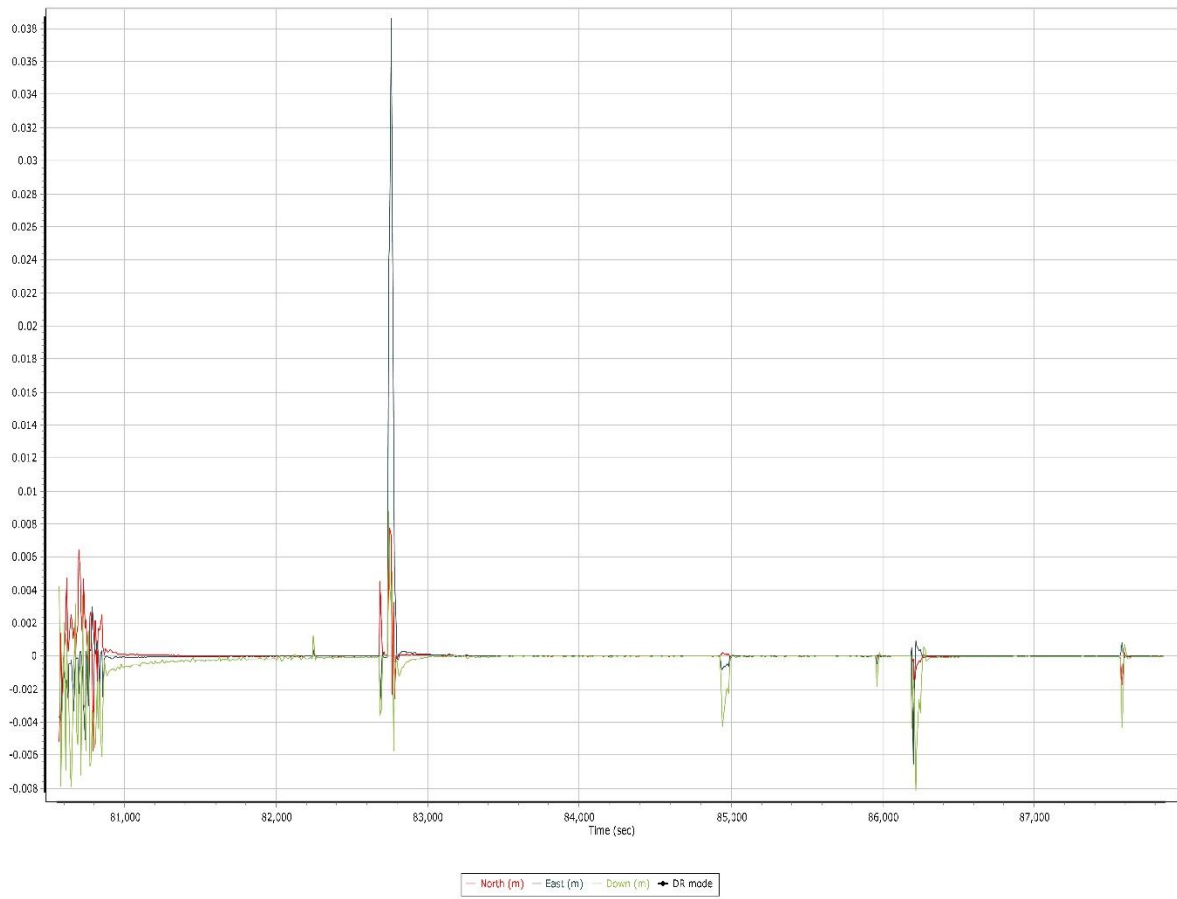


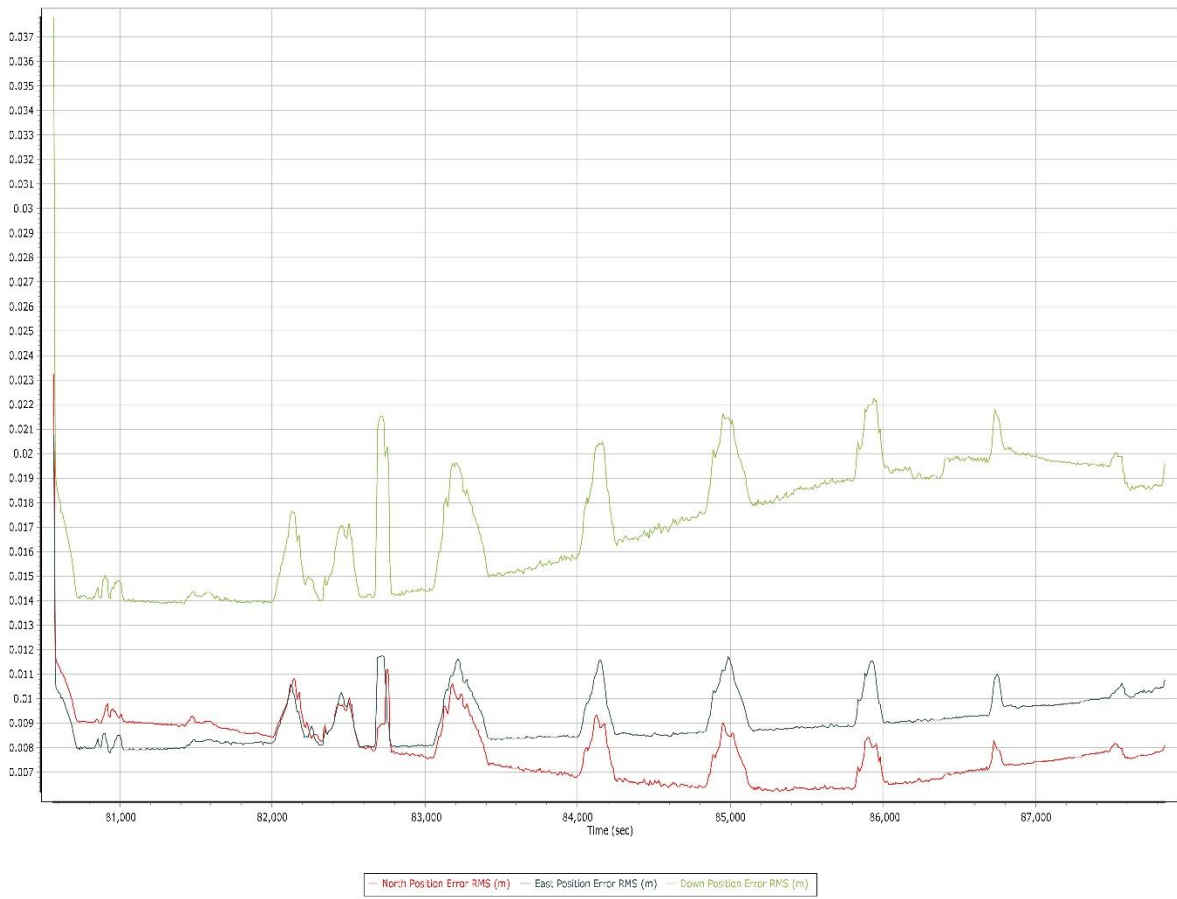


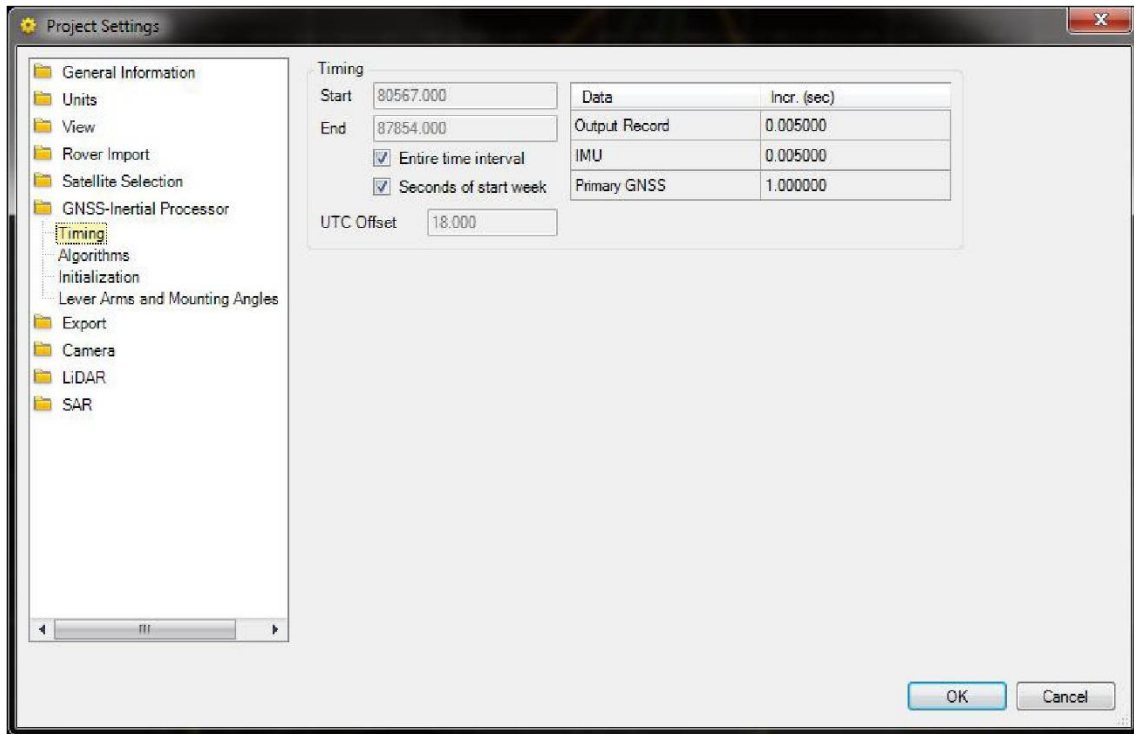


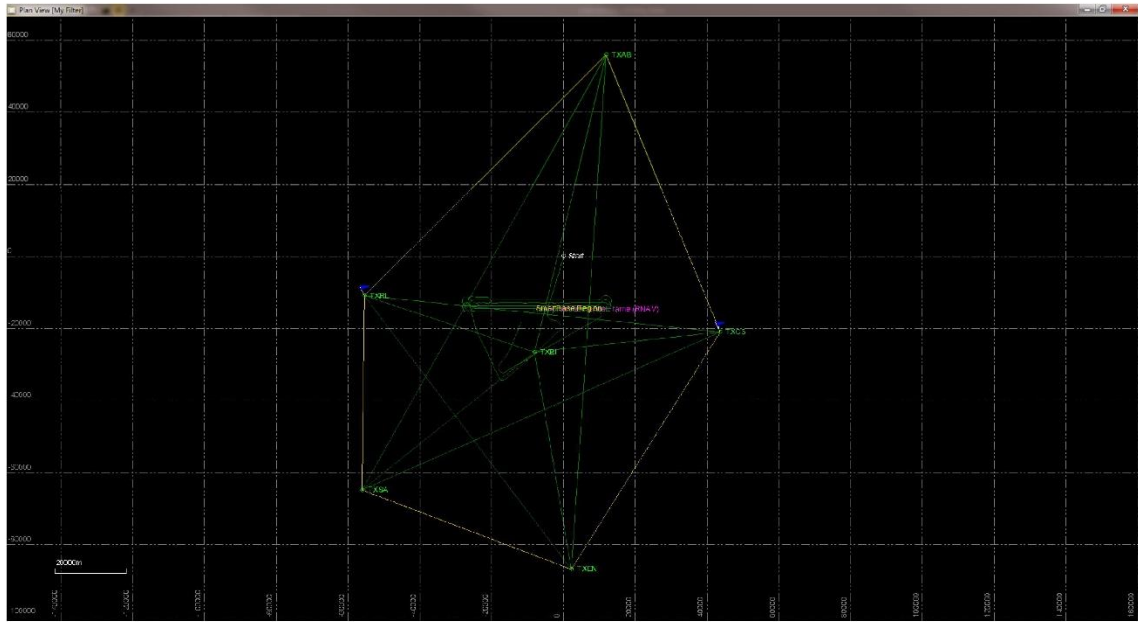


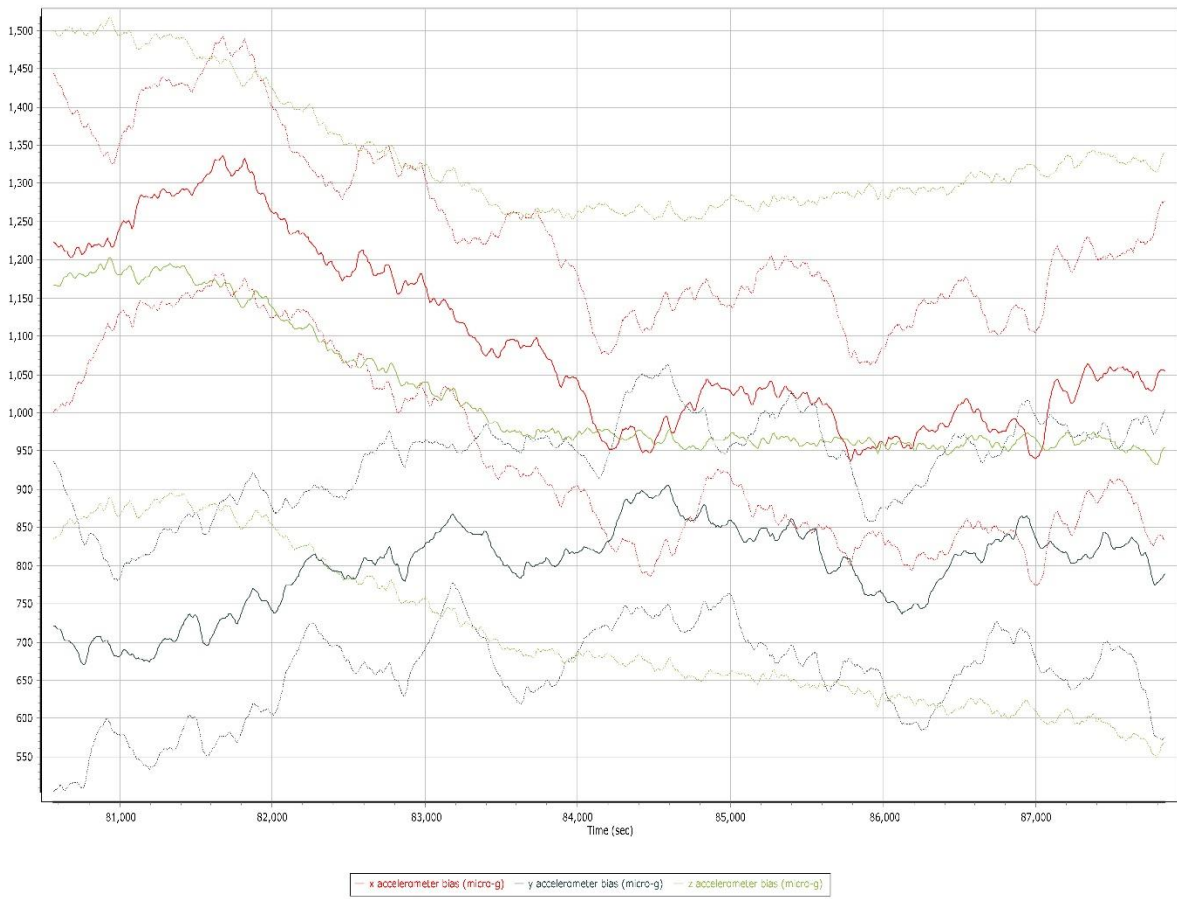
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IA PPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

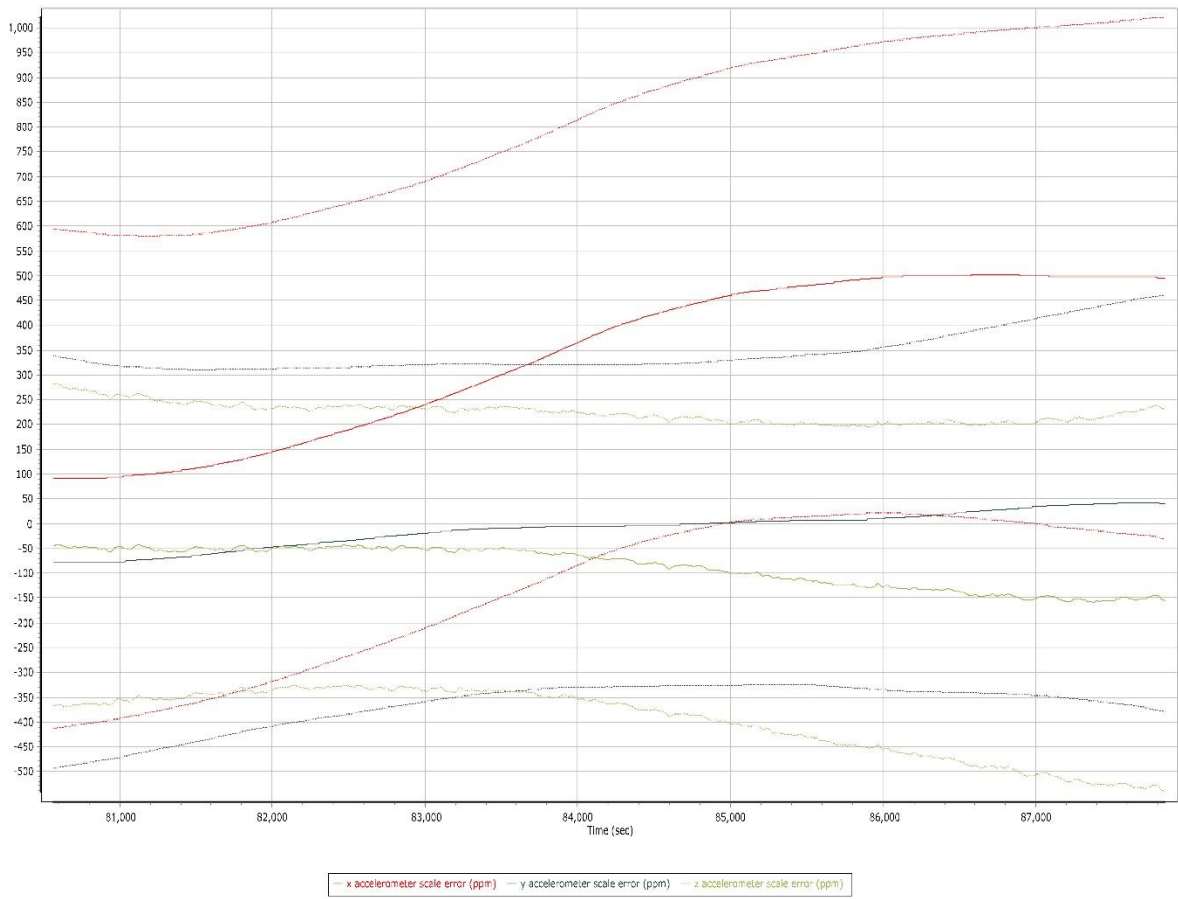


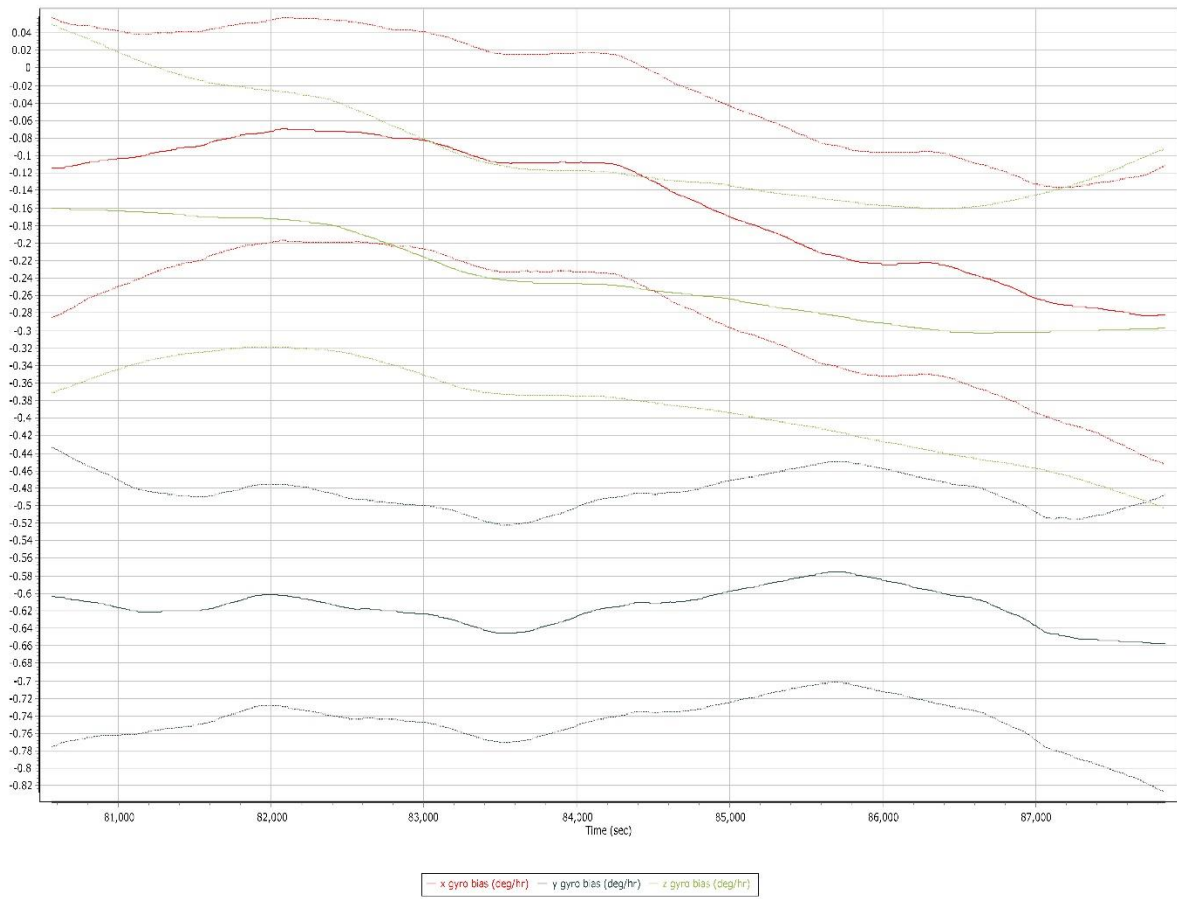


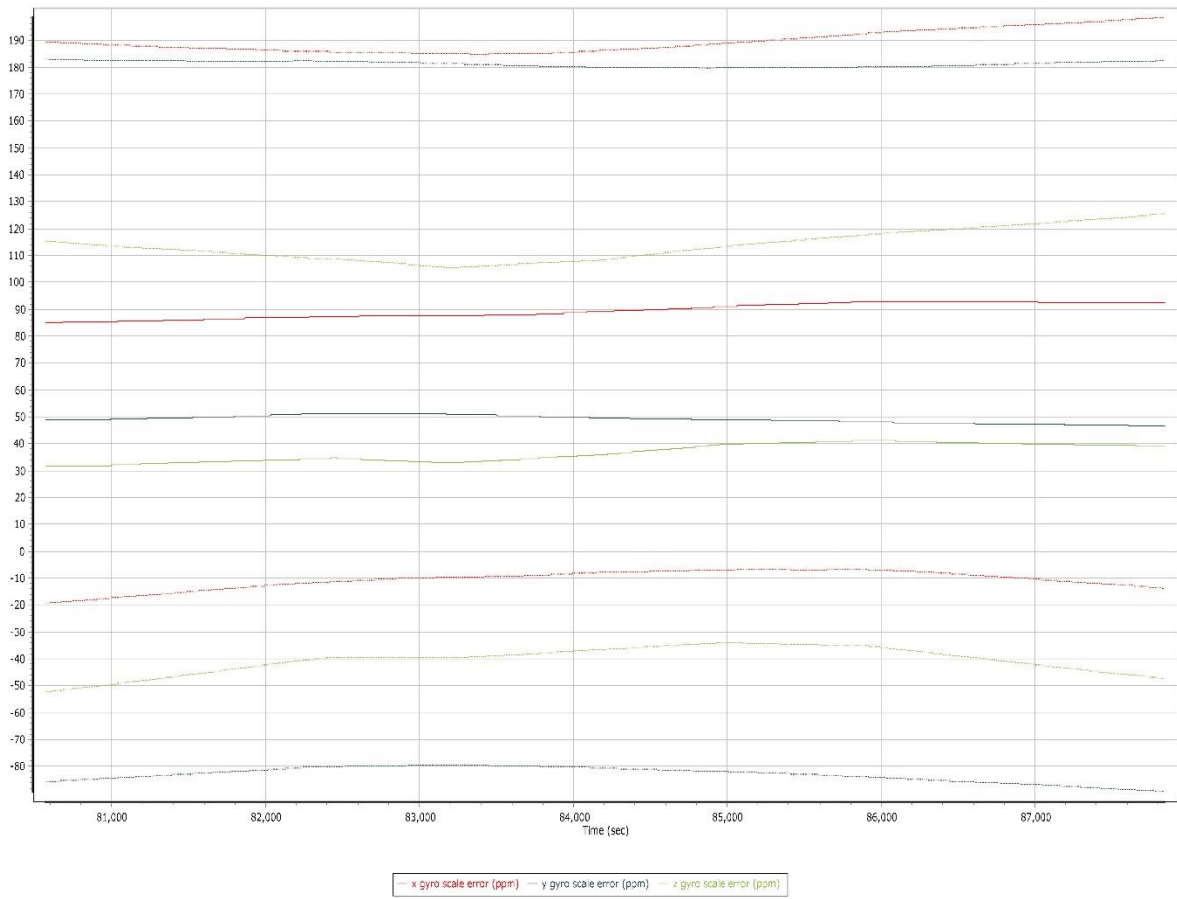




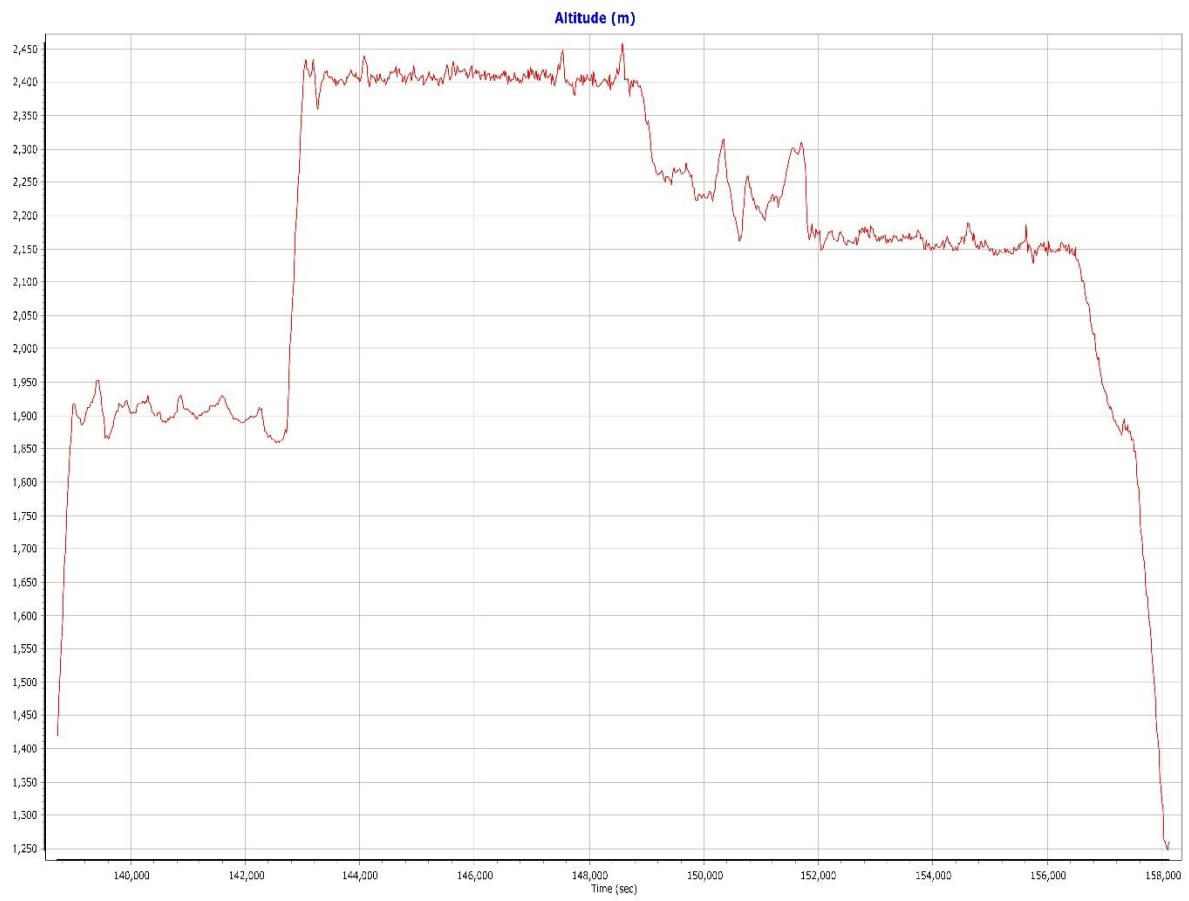


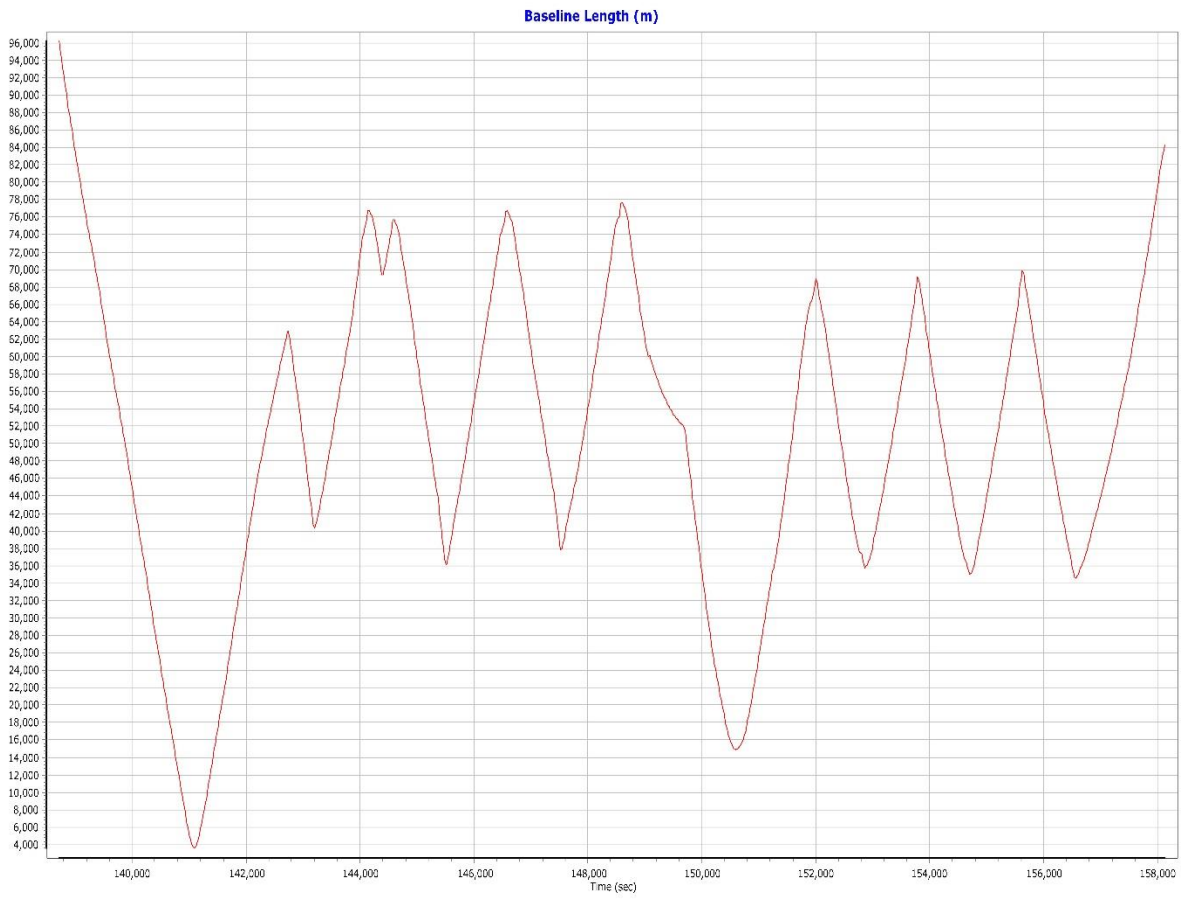


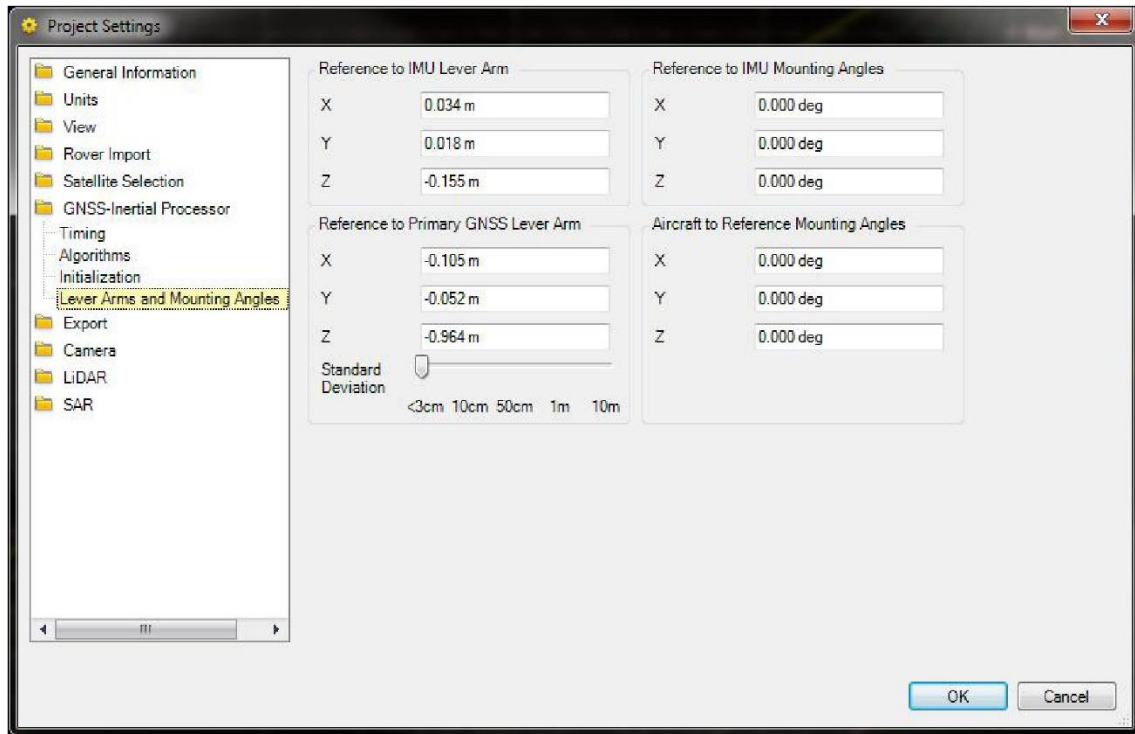


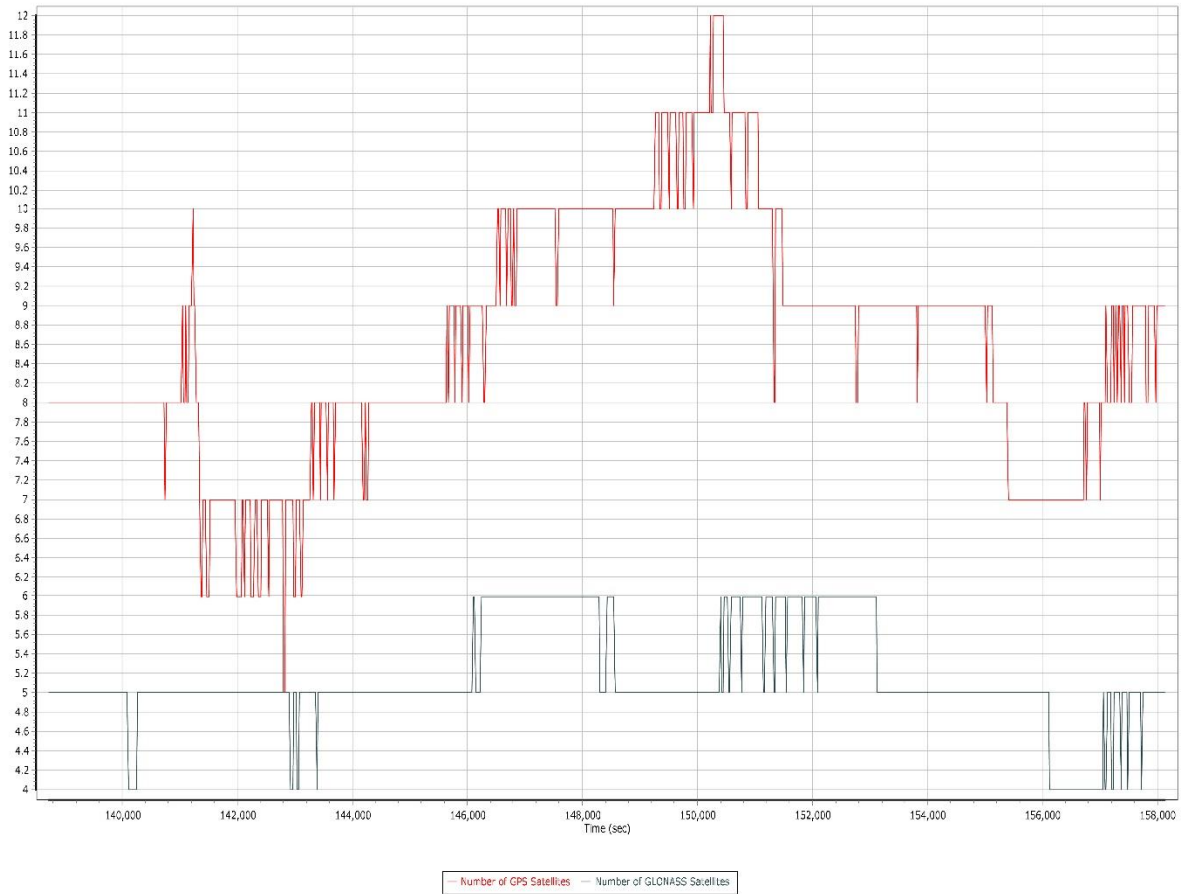


UNB18043A

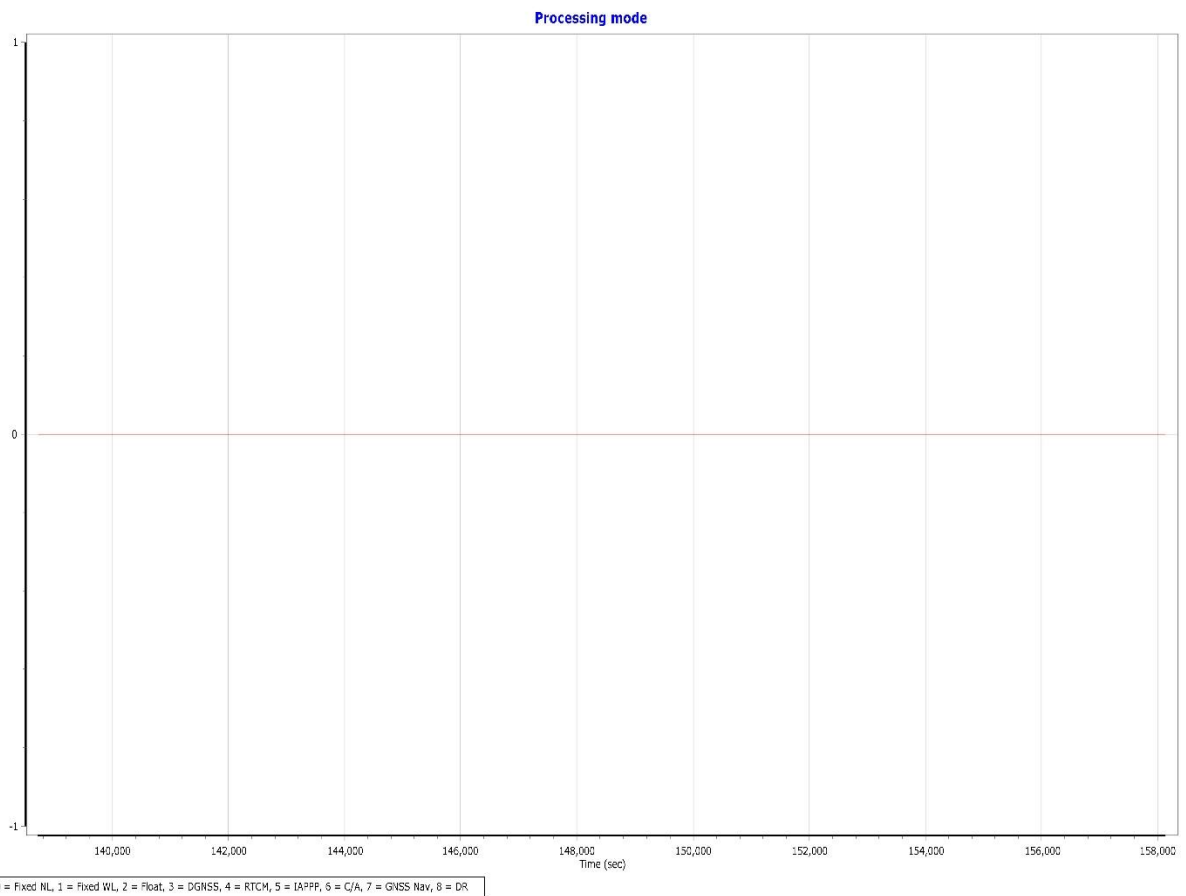


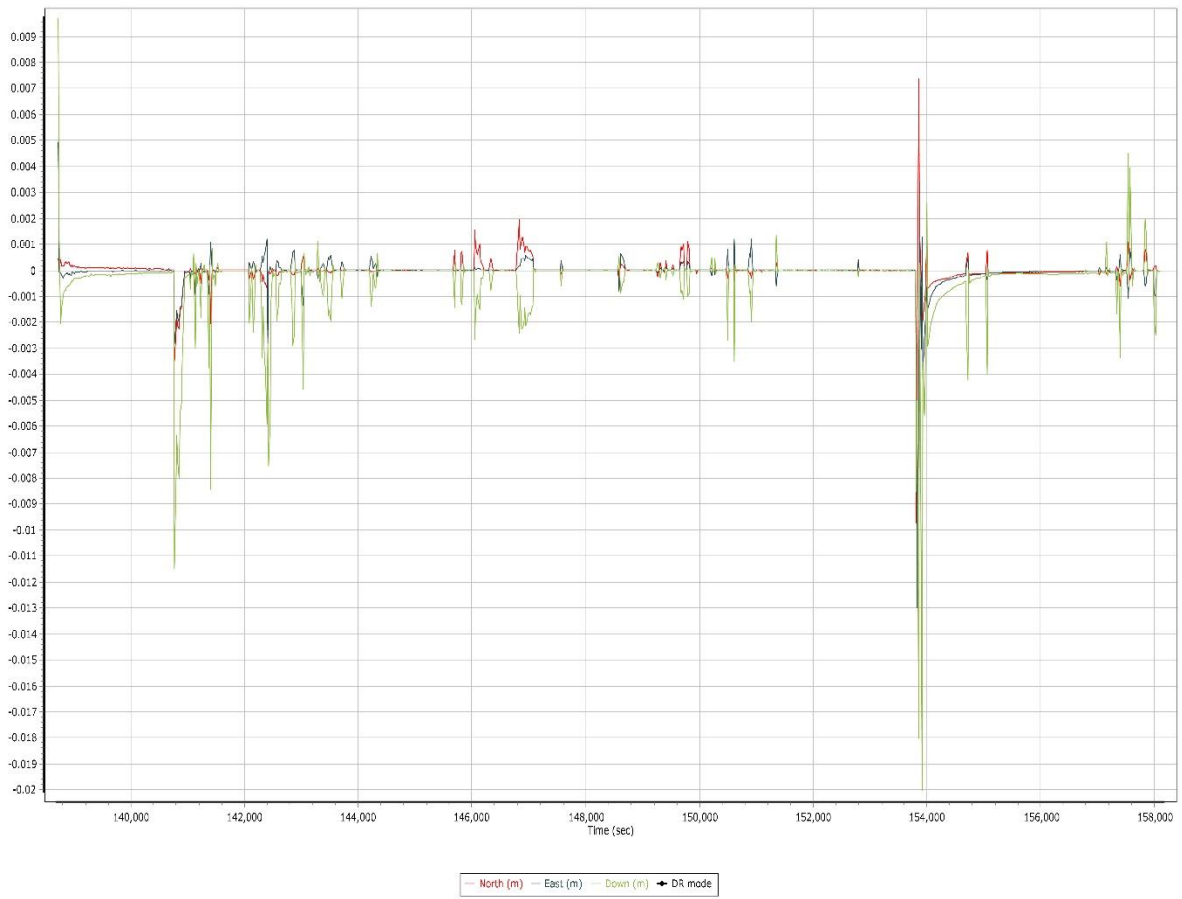


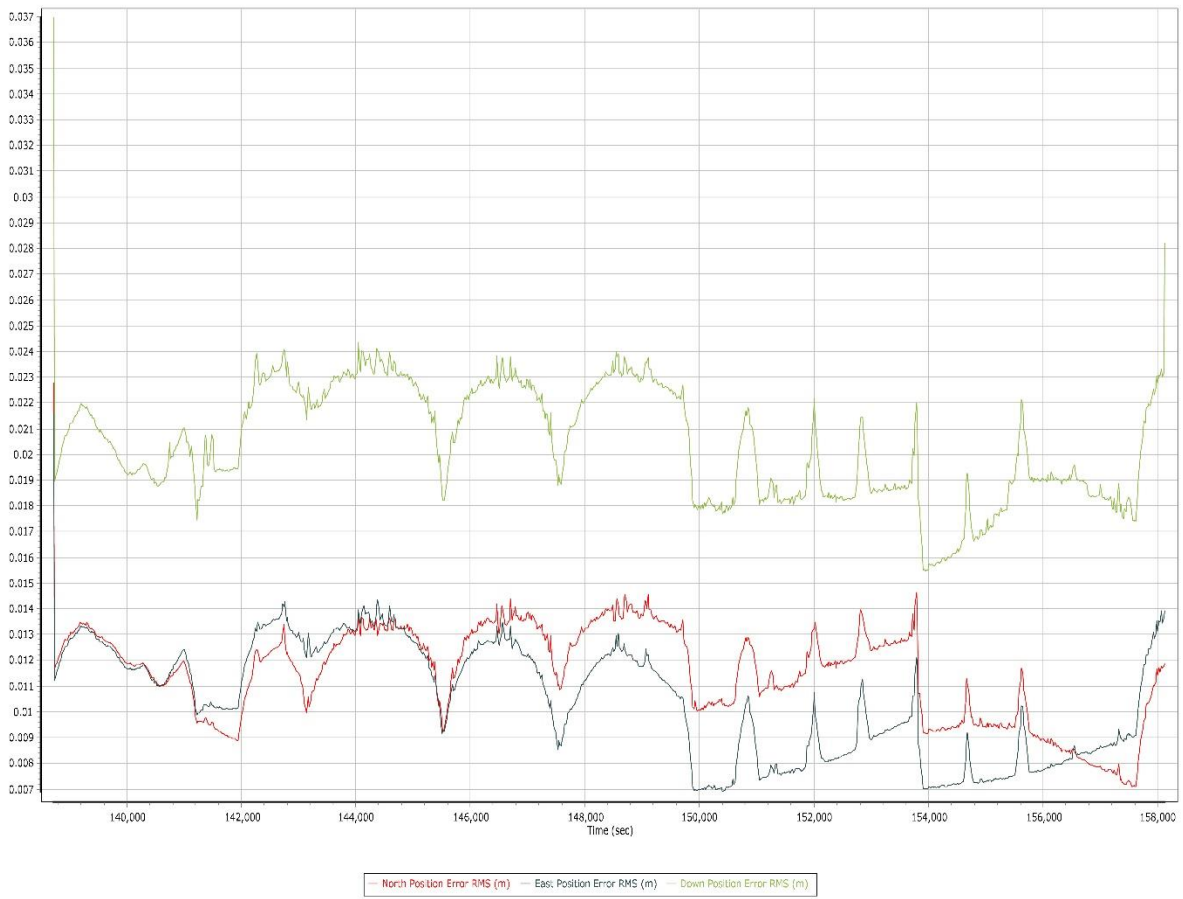


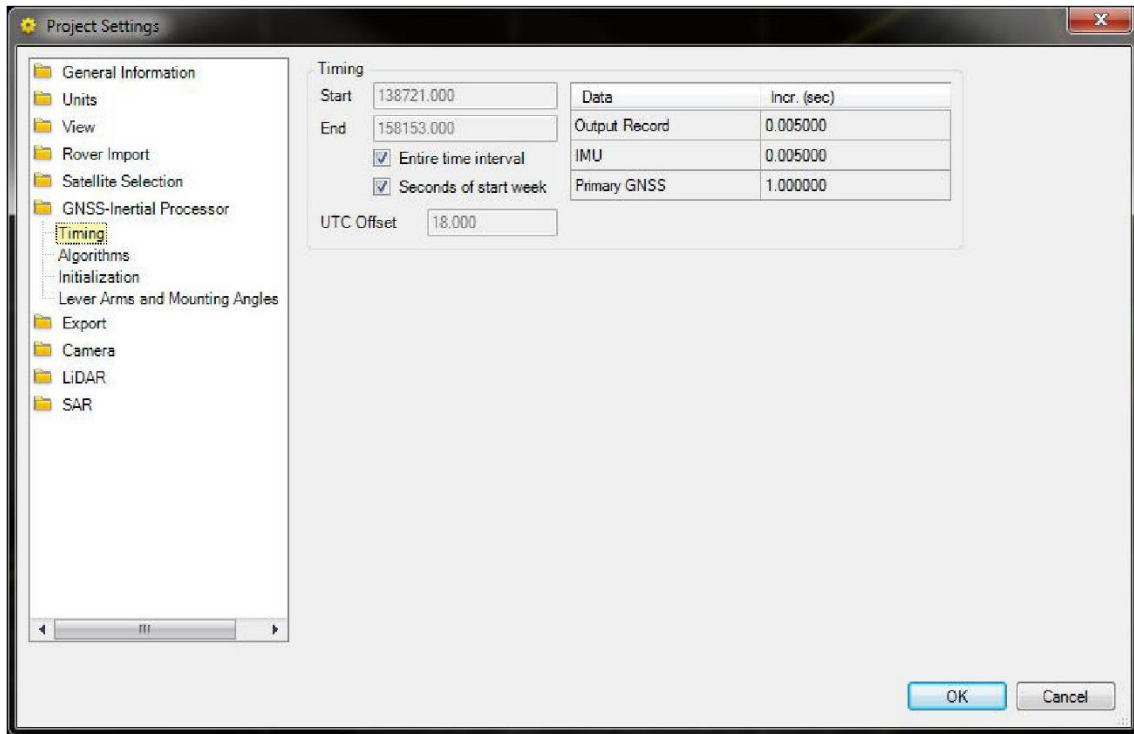


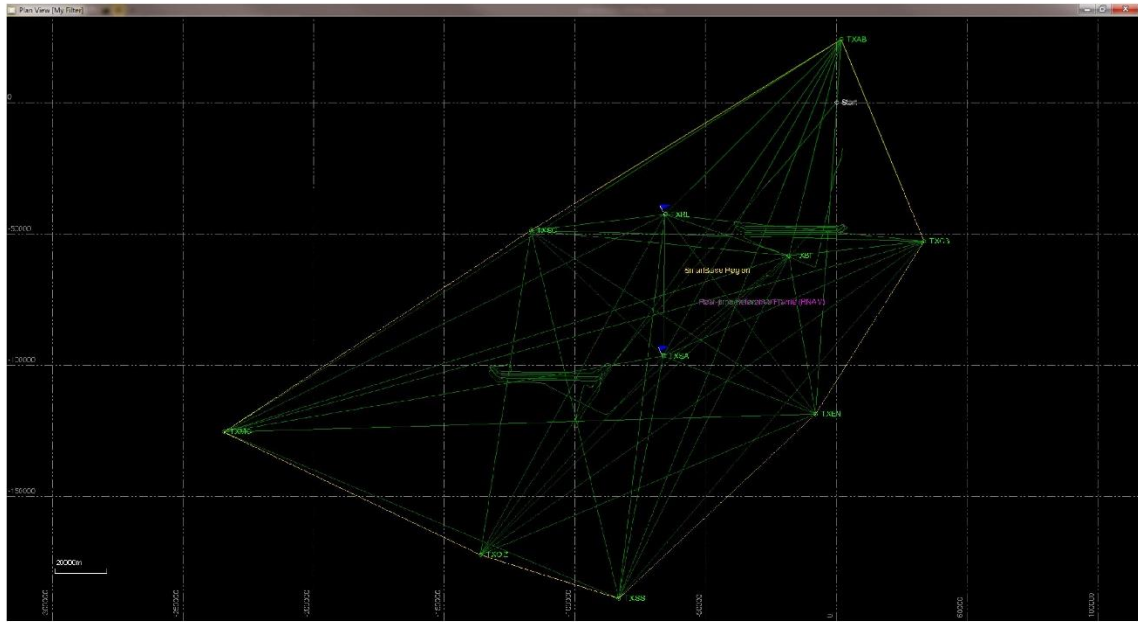


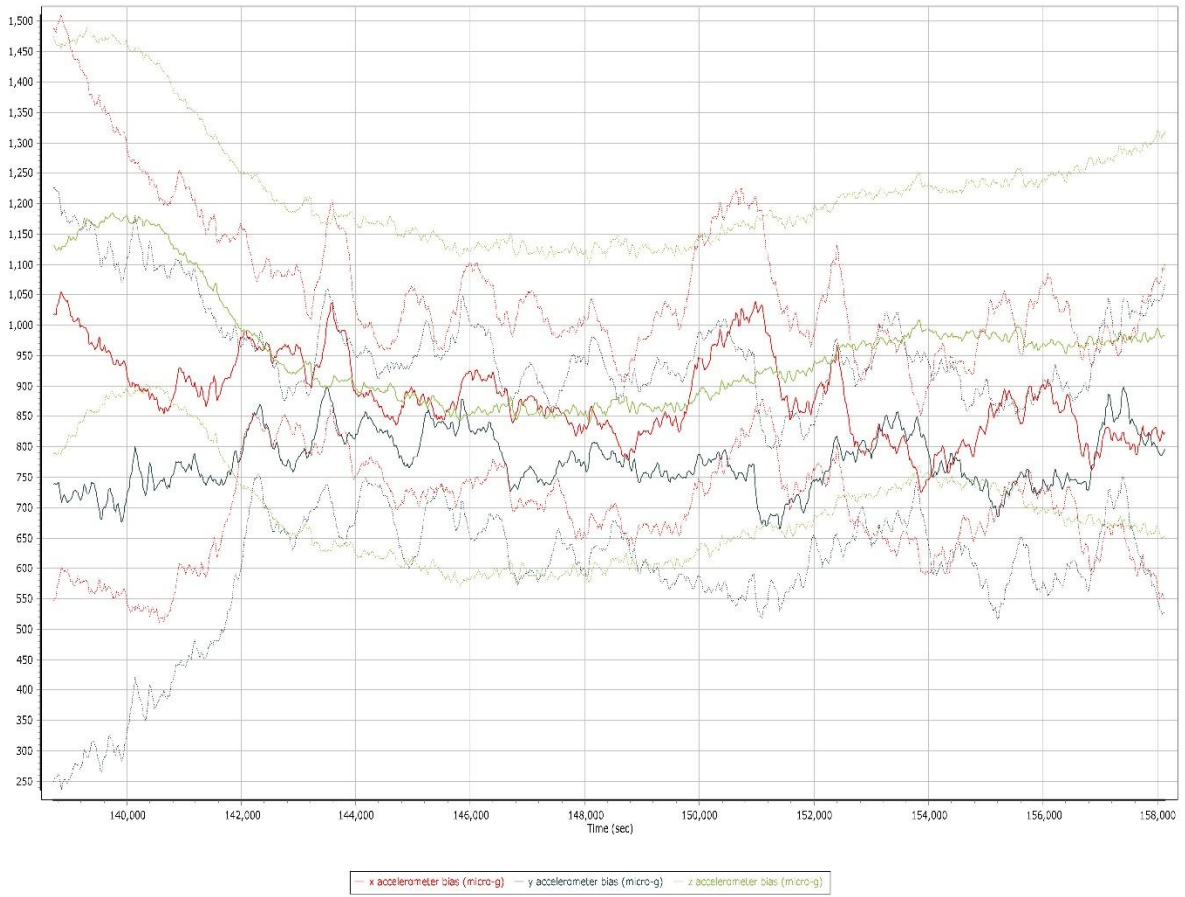


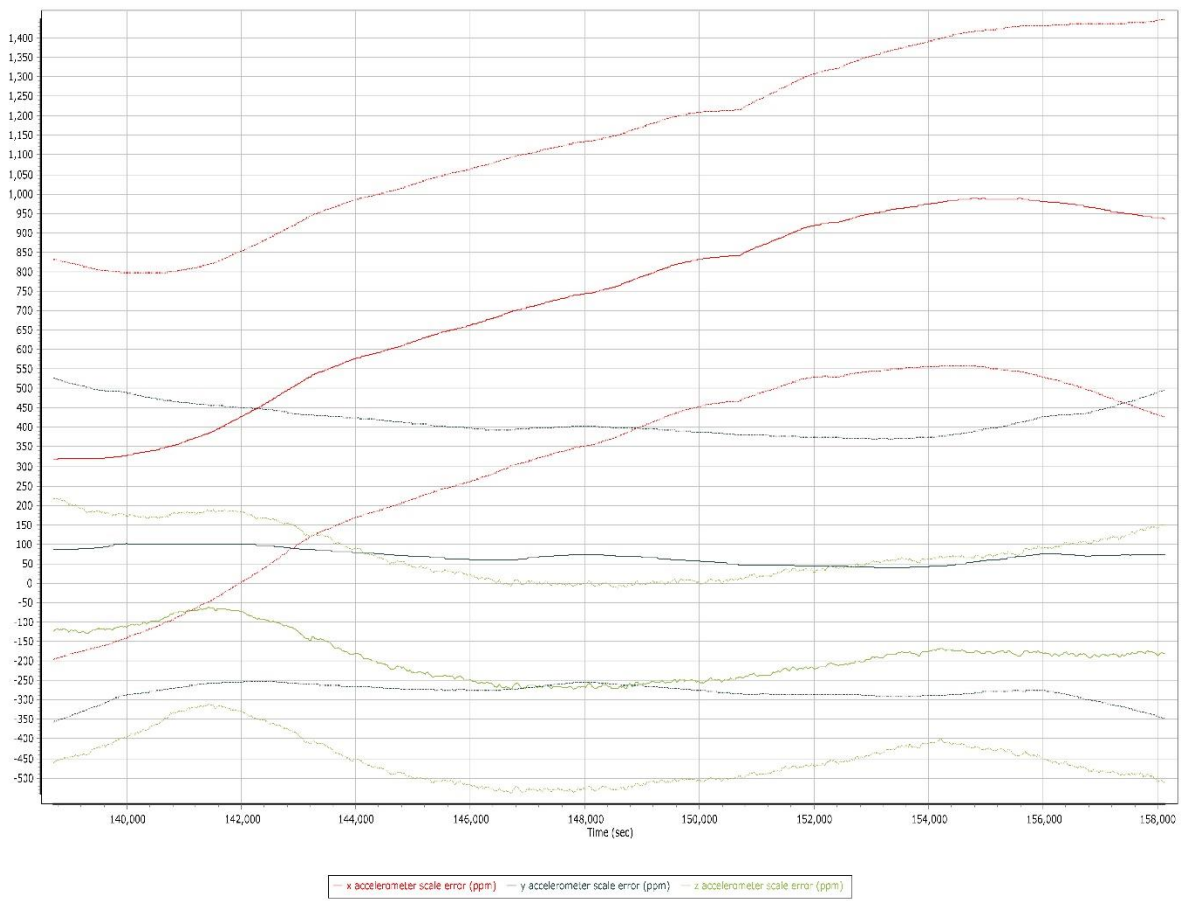


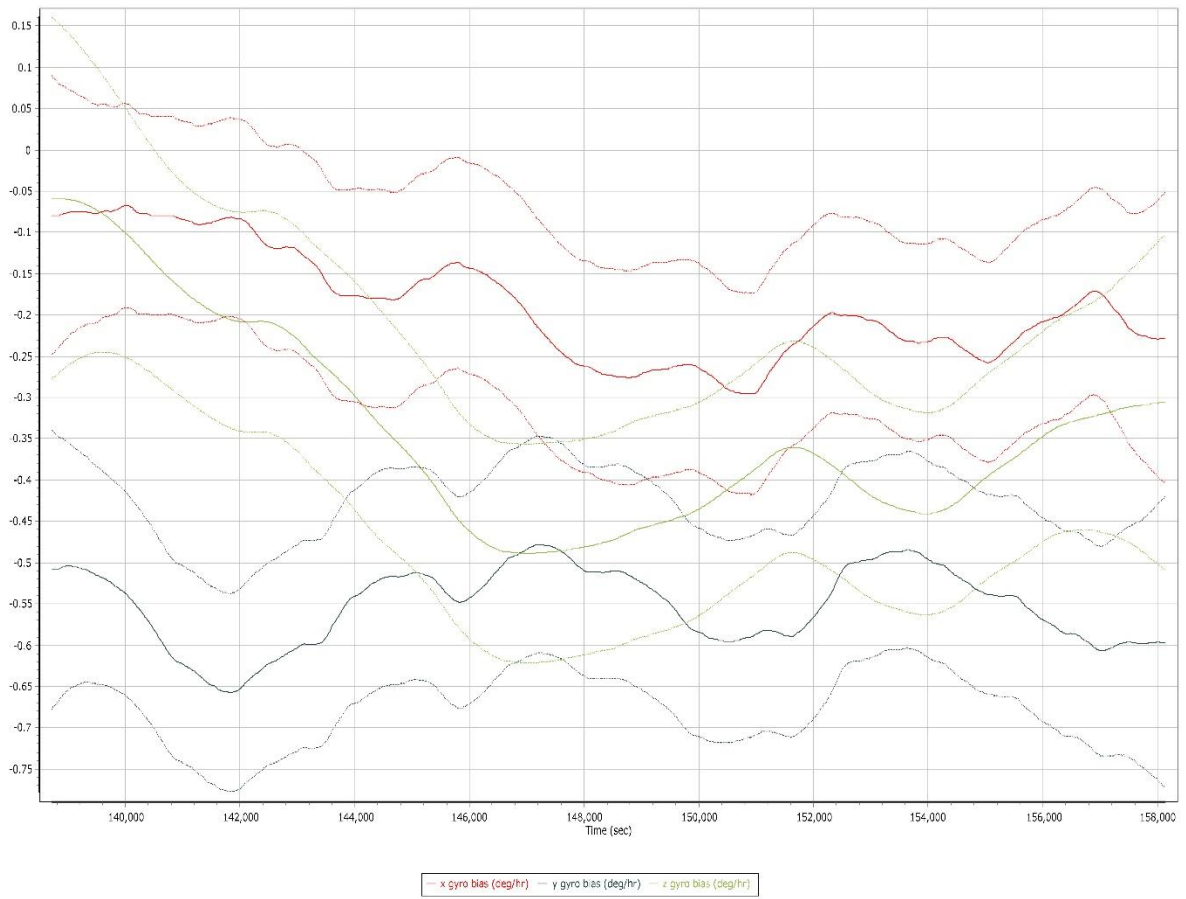


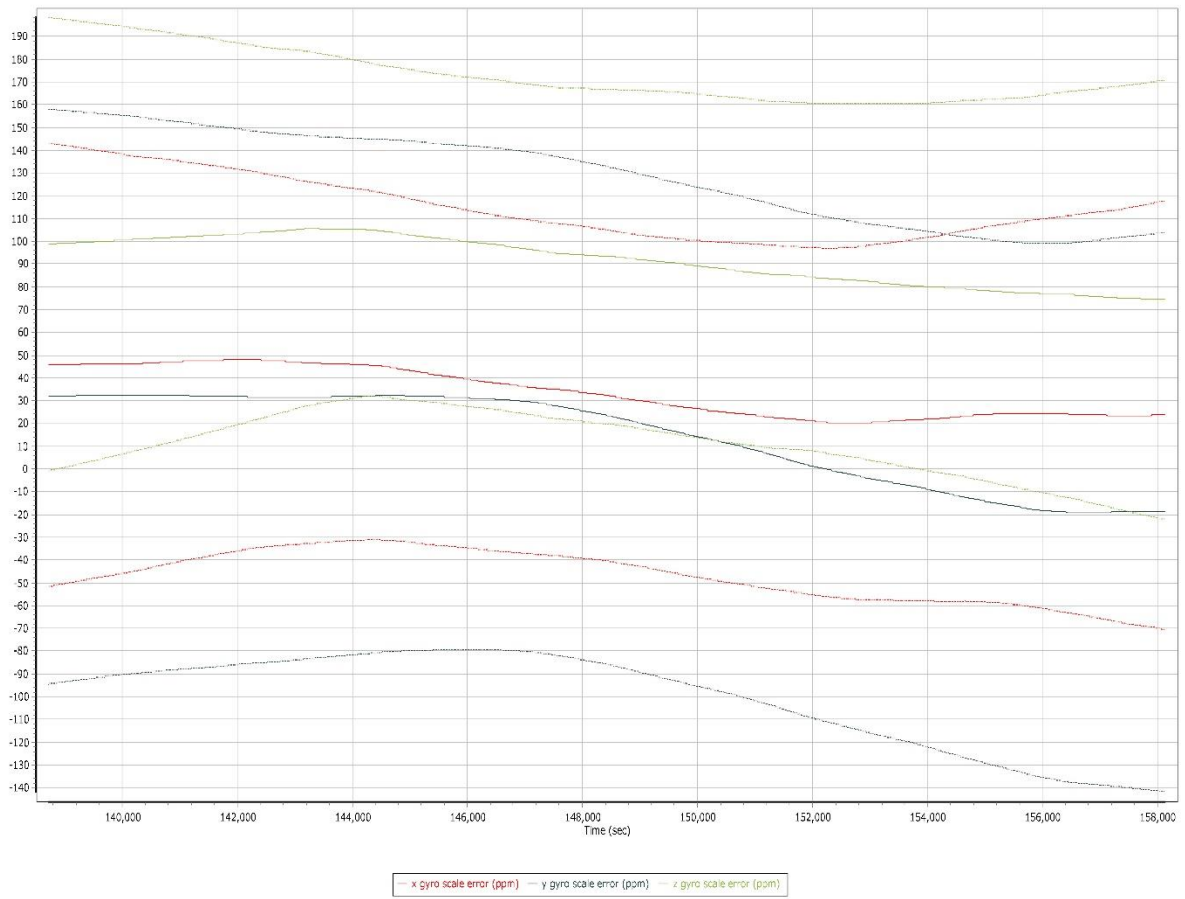






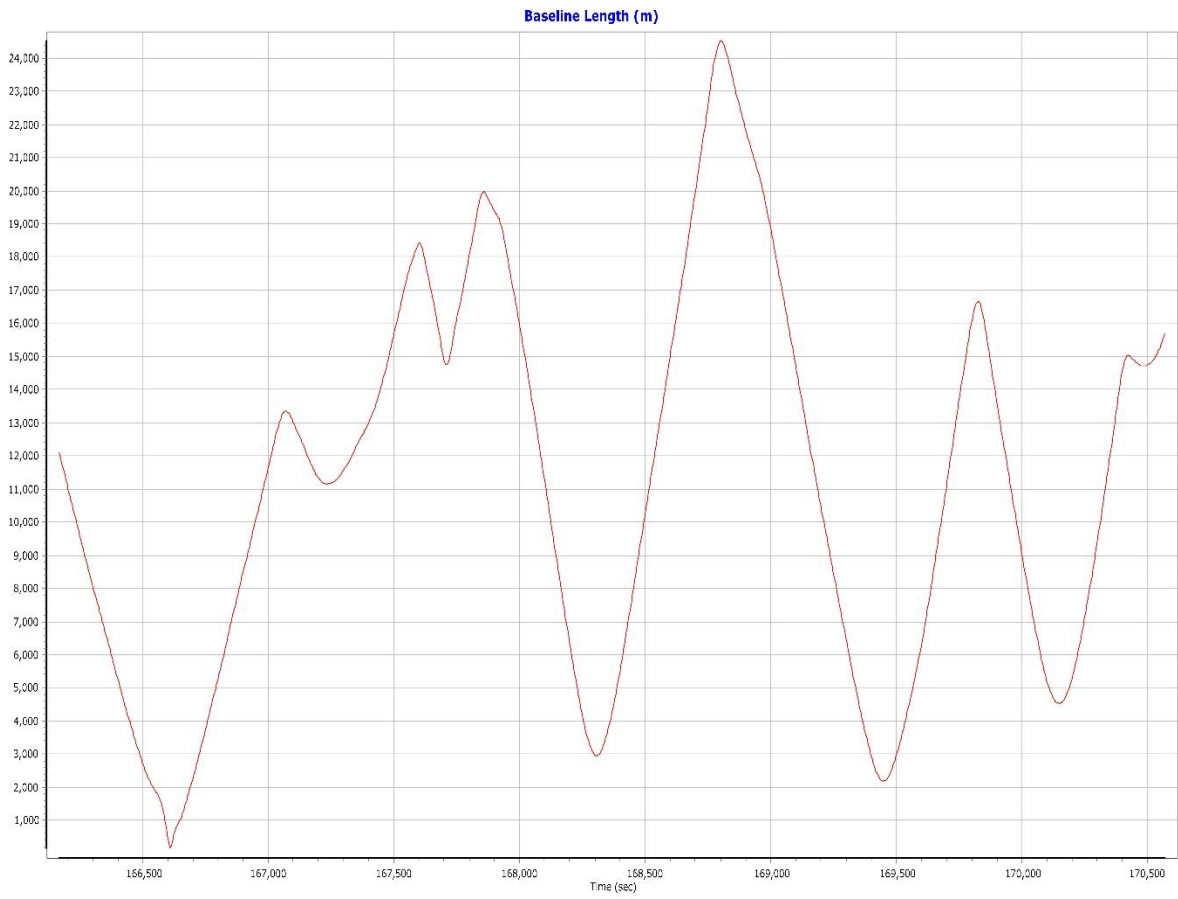


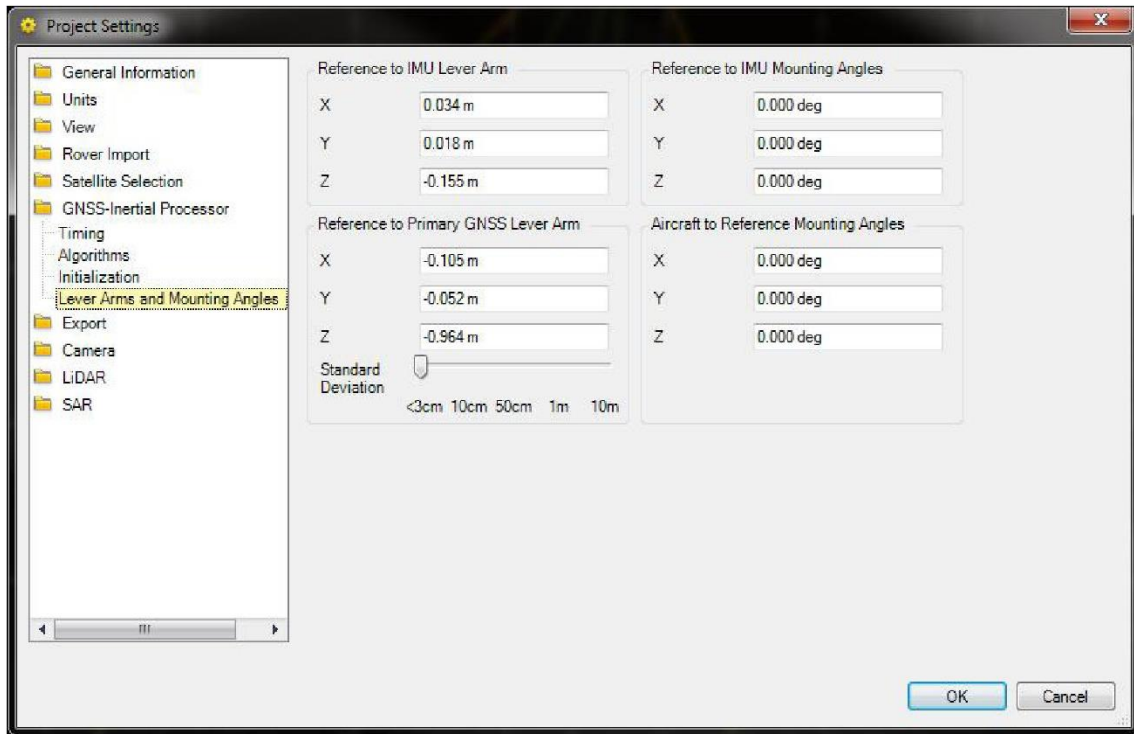


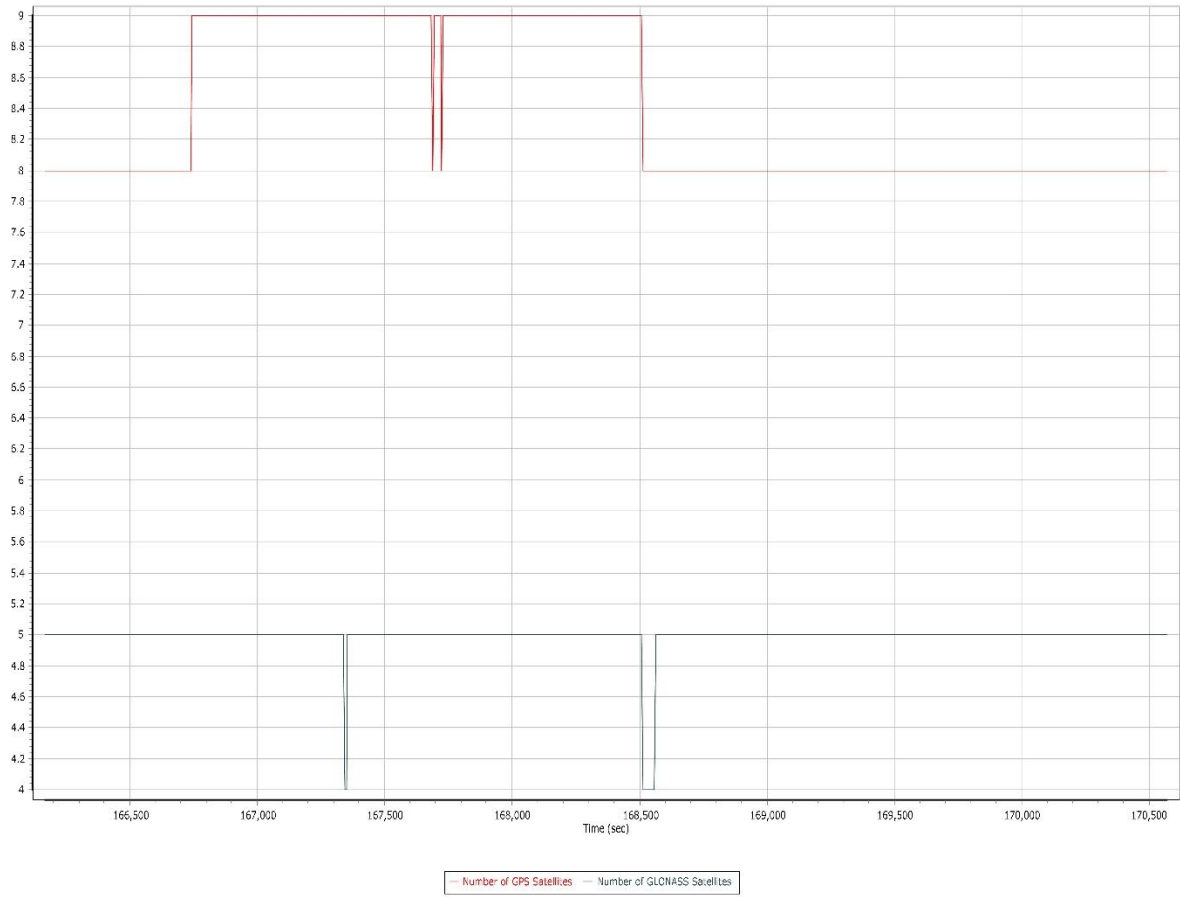


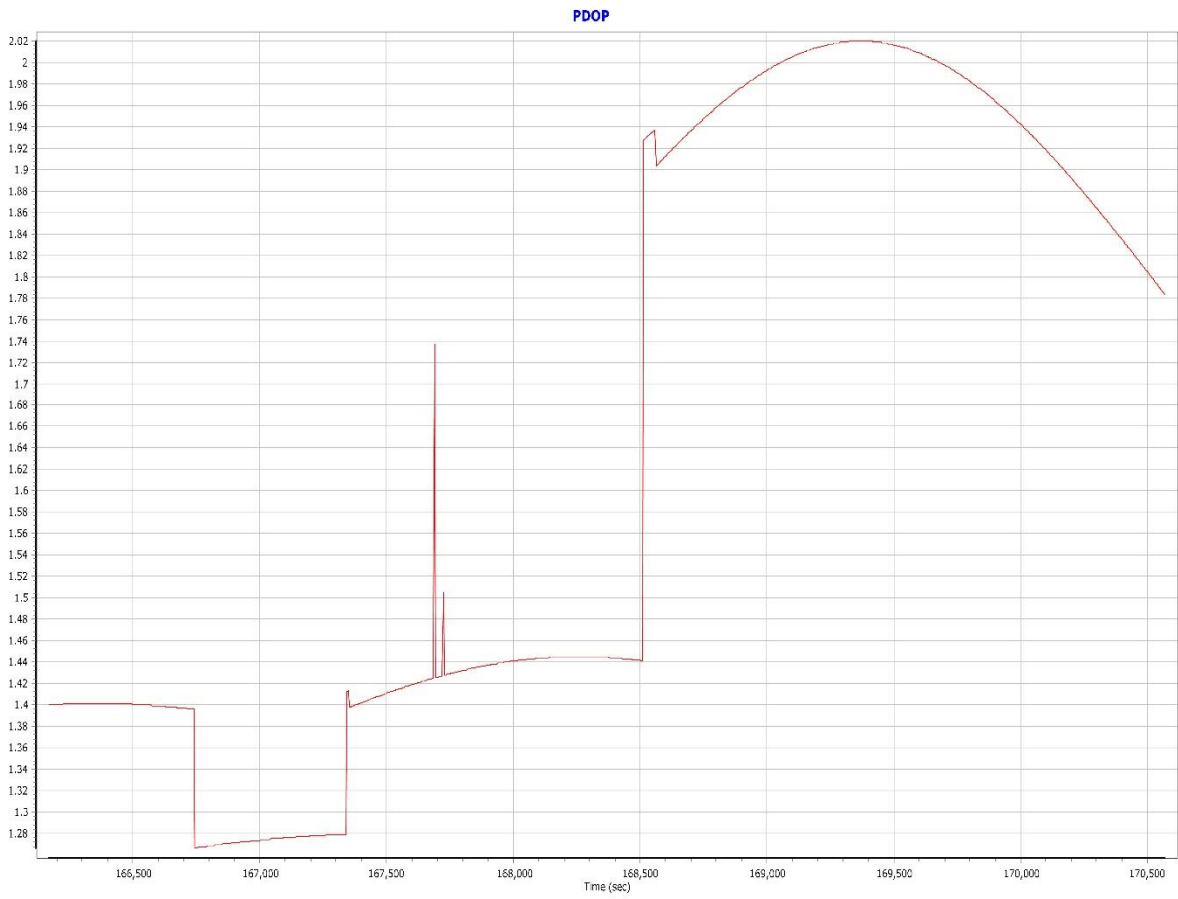
UNB18043B



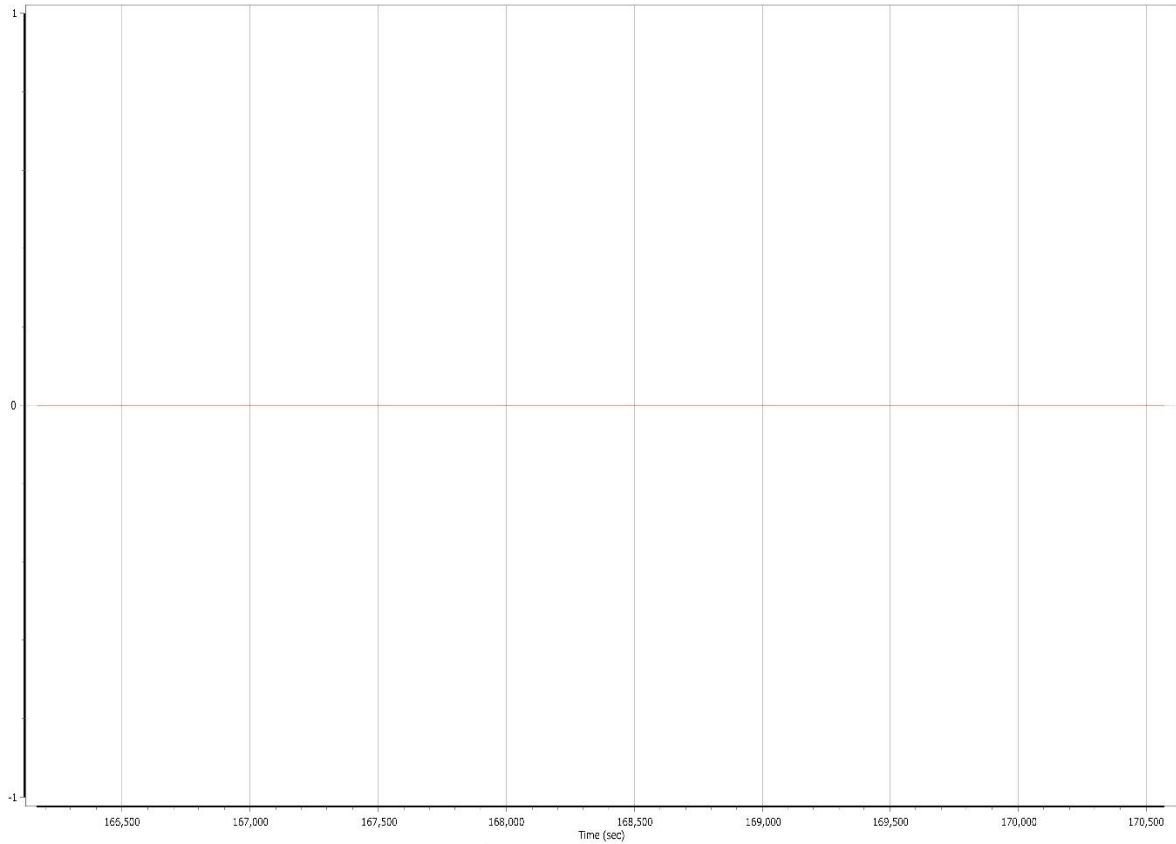




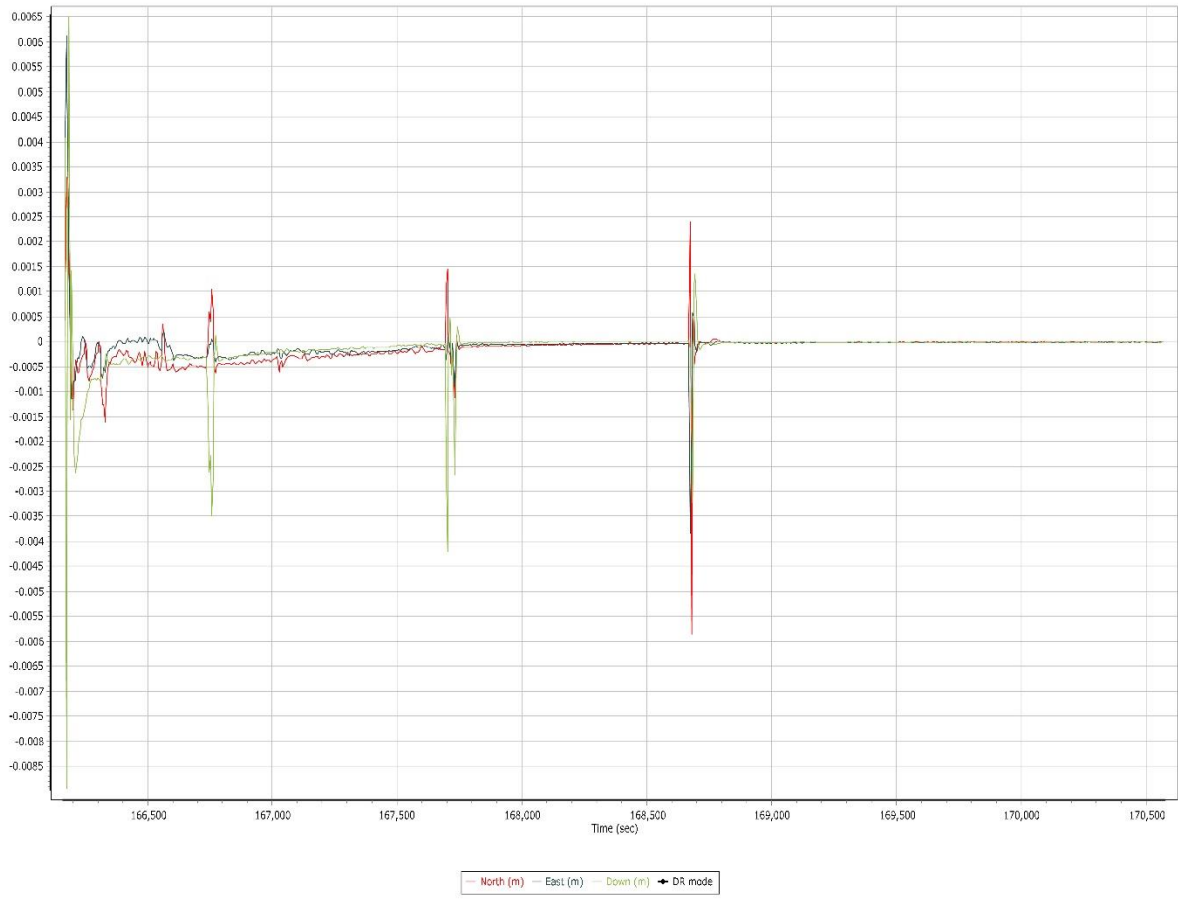


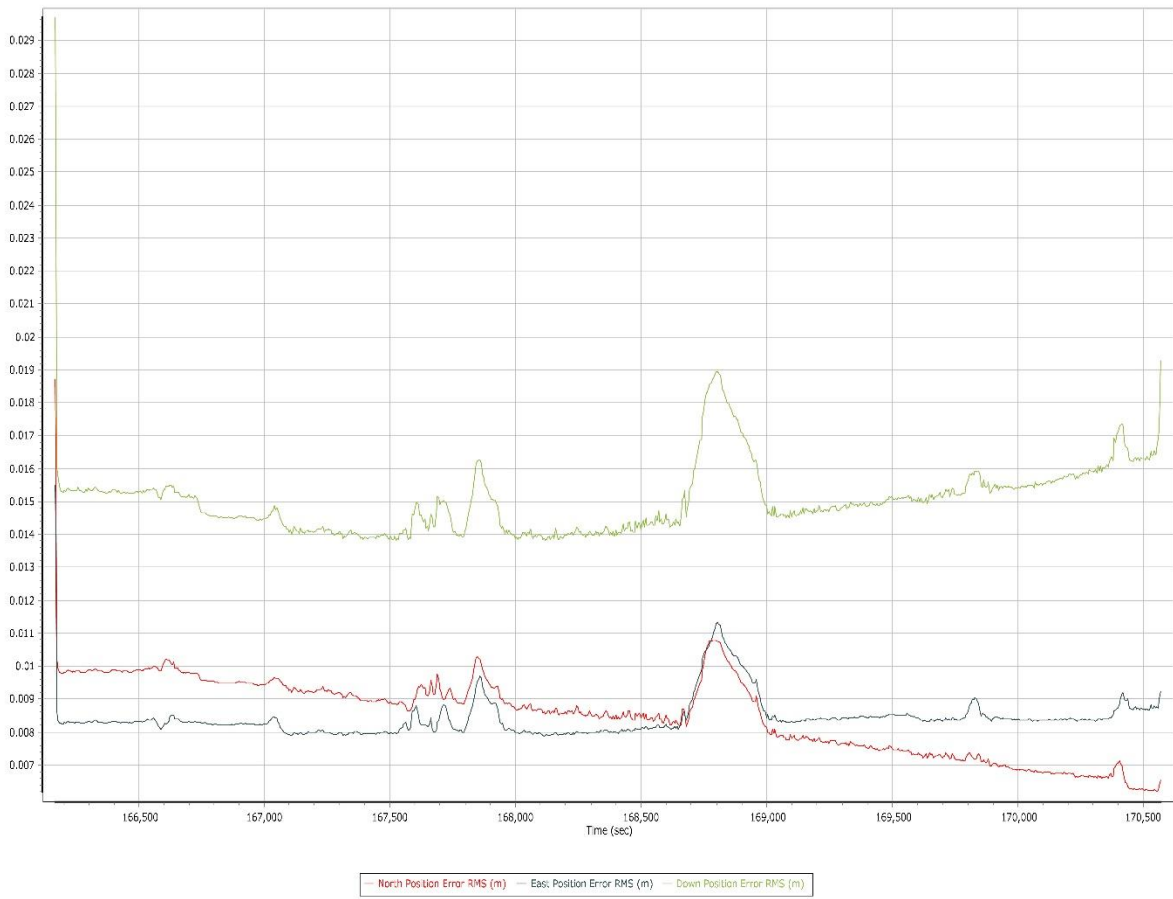


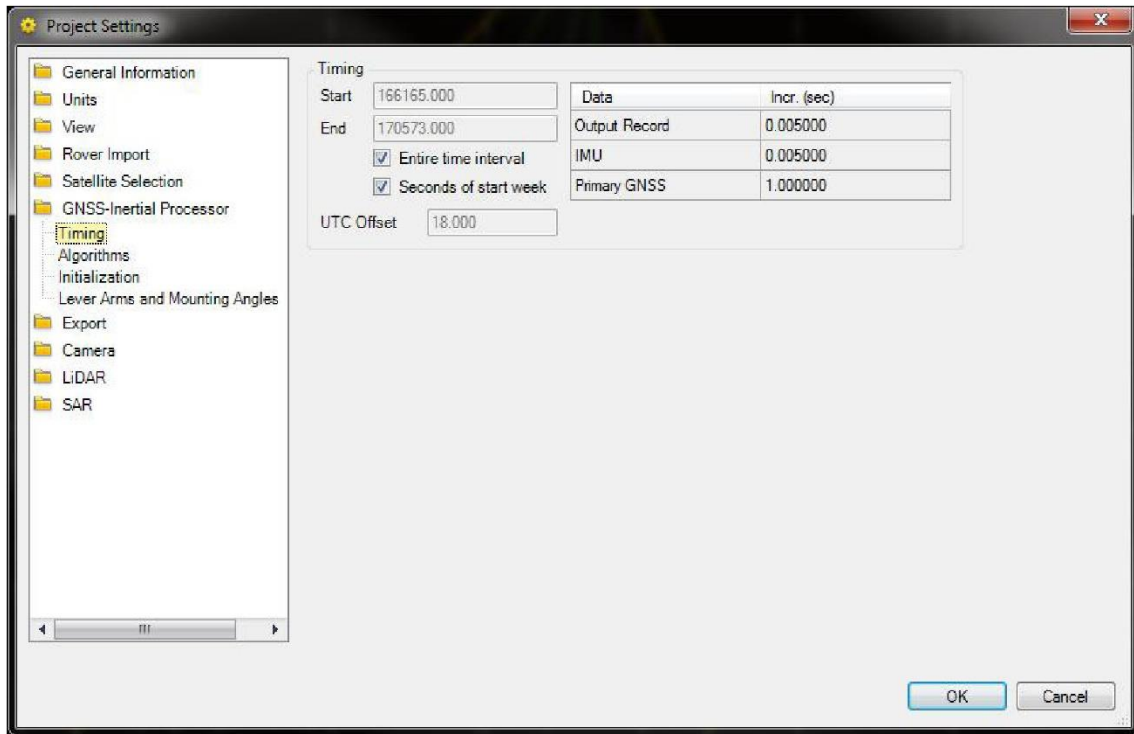
Processing mode

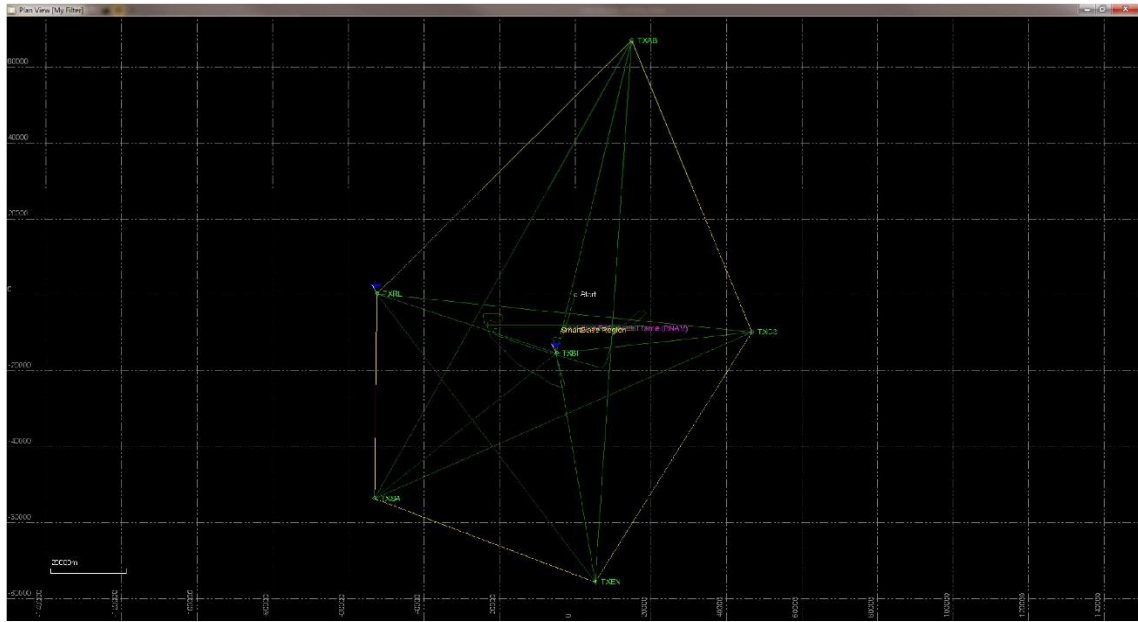


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IA*PPF, 6 = C/A, 7 = GNSS Nav, 8 = DR

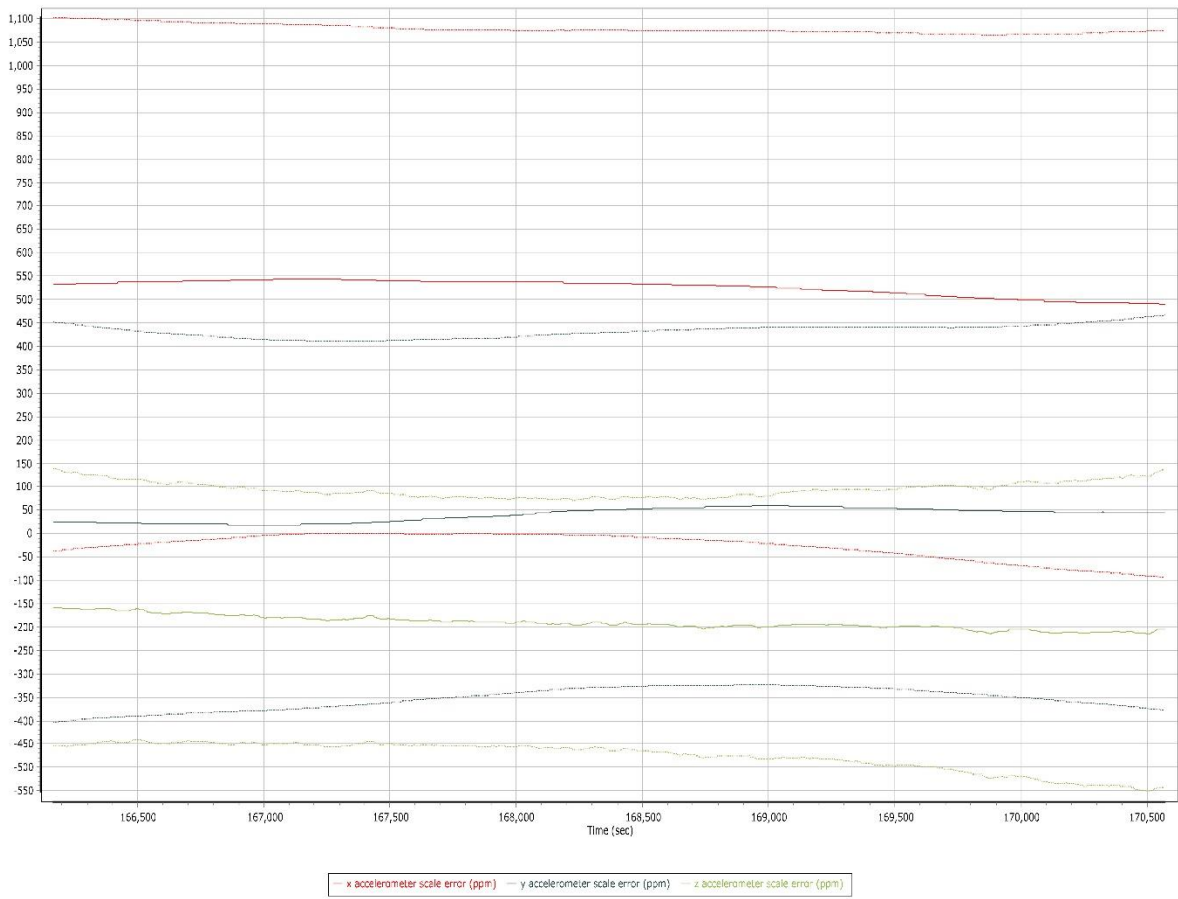


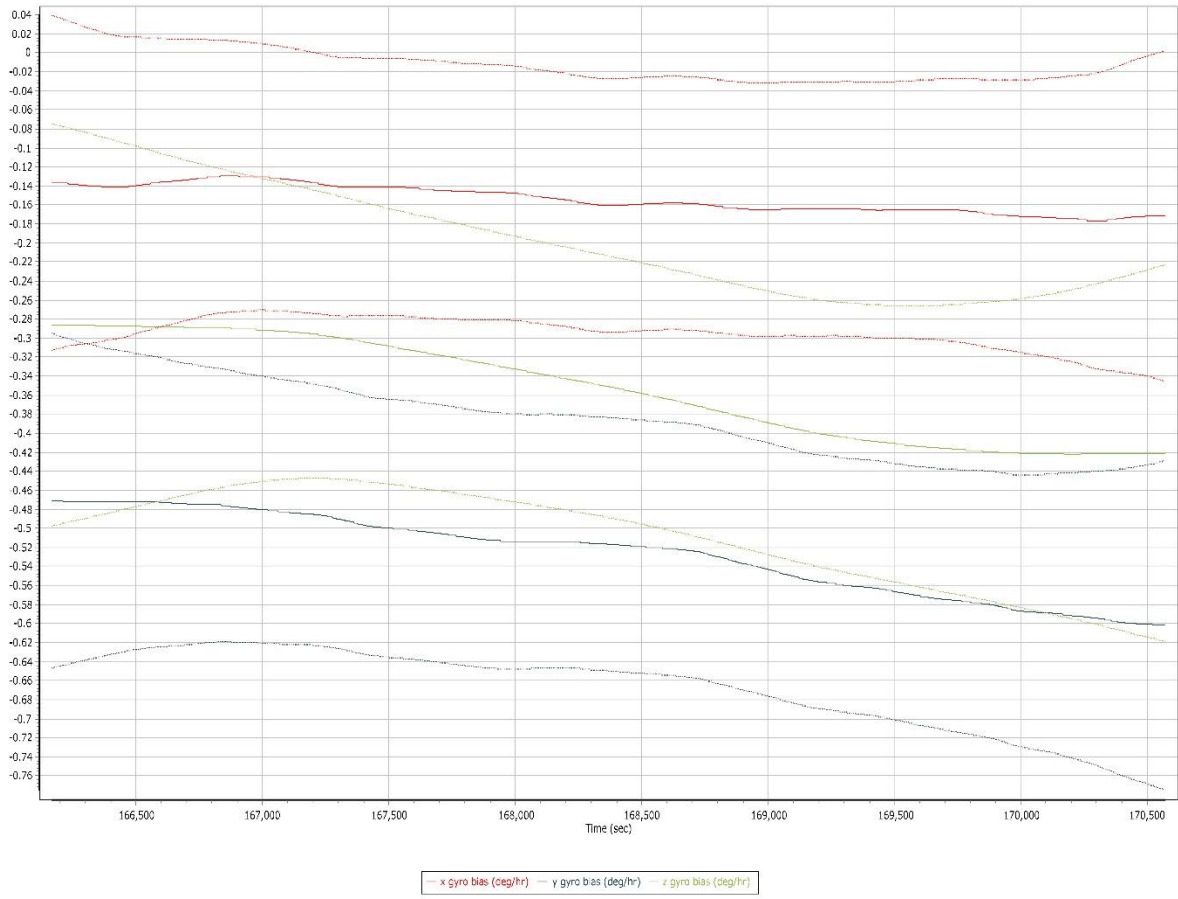


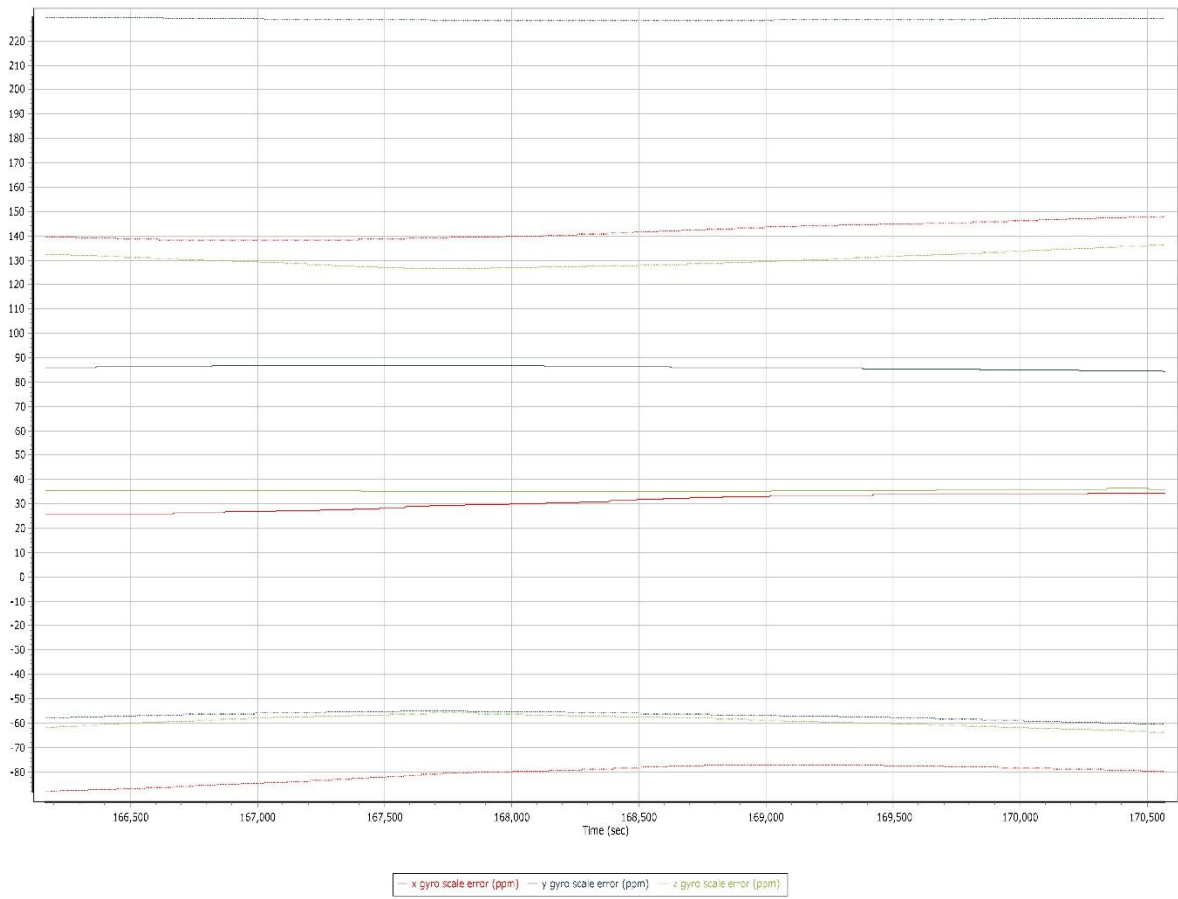




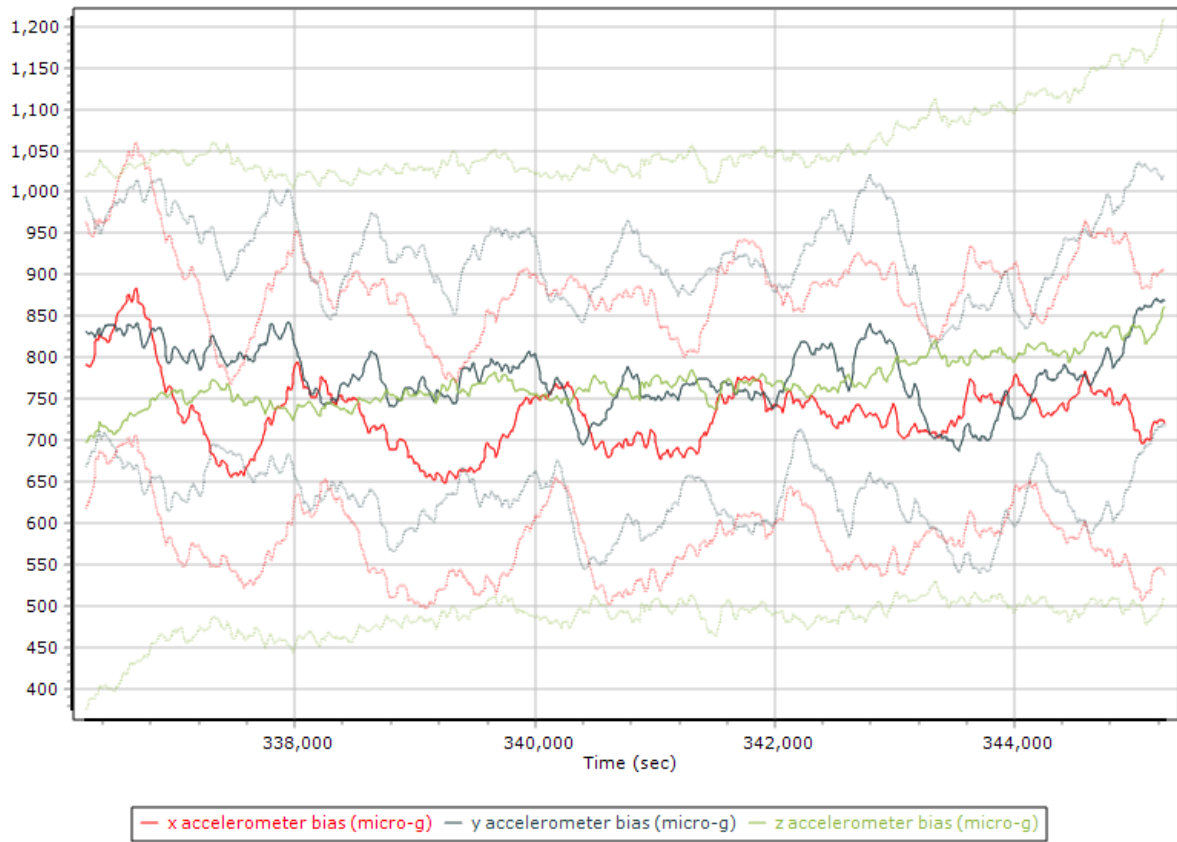


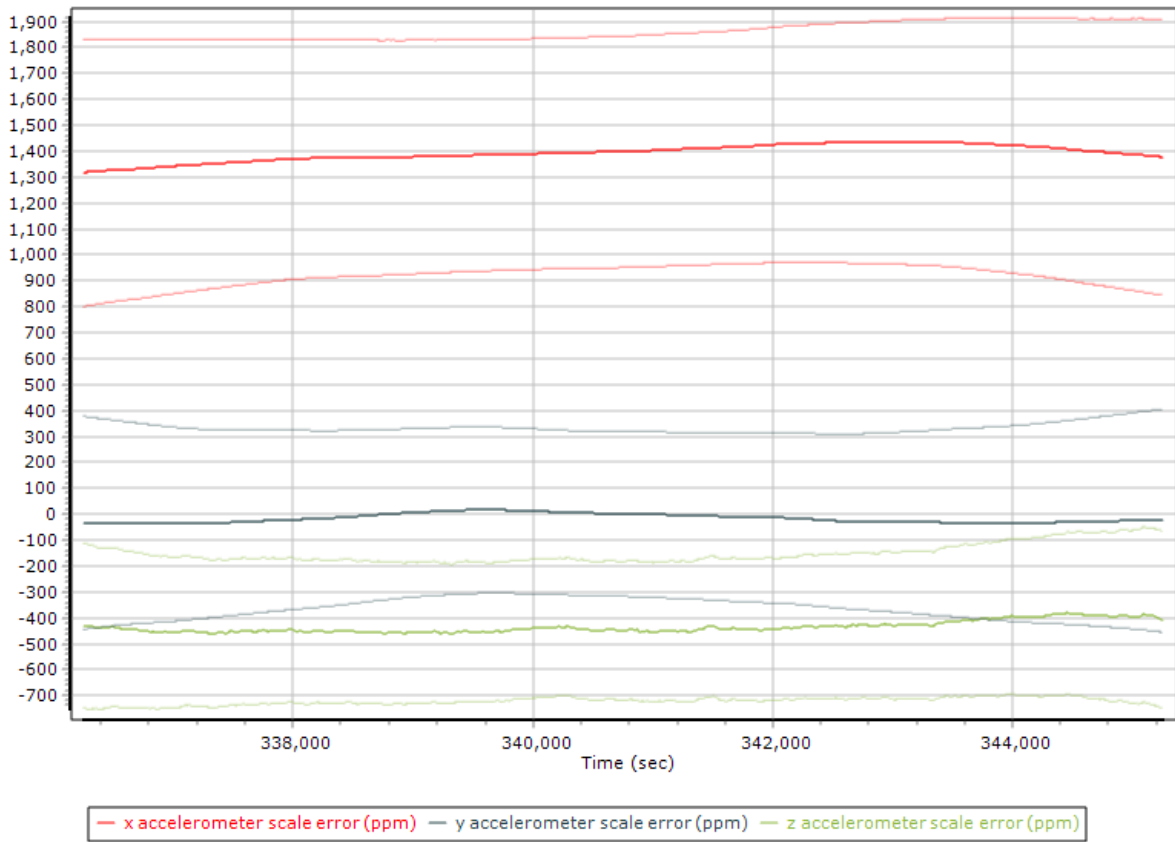


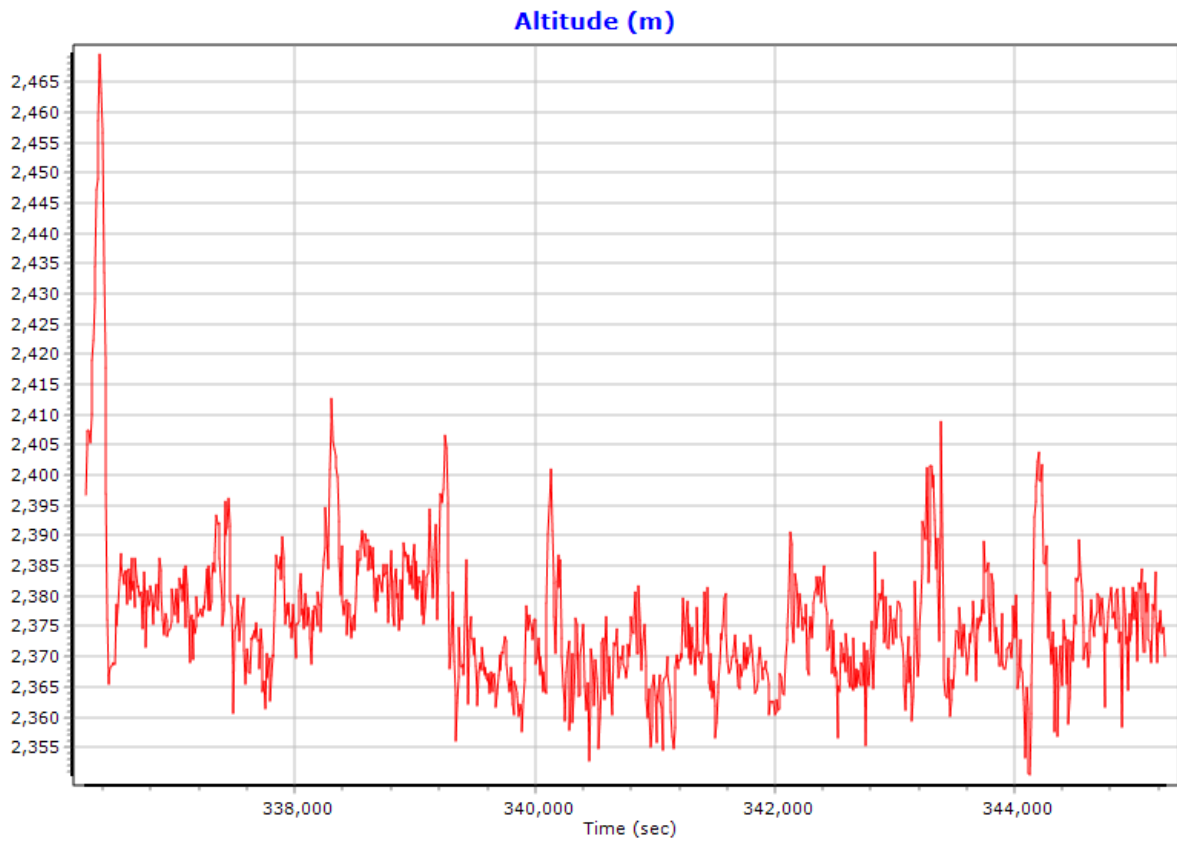


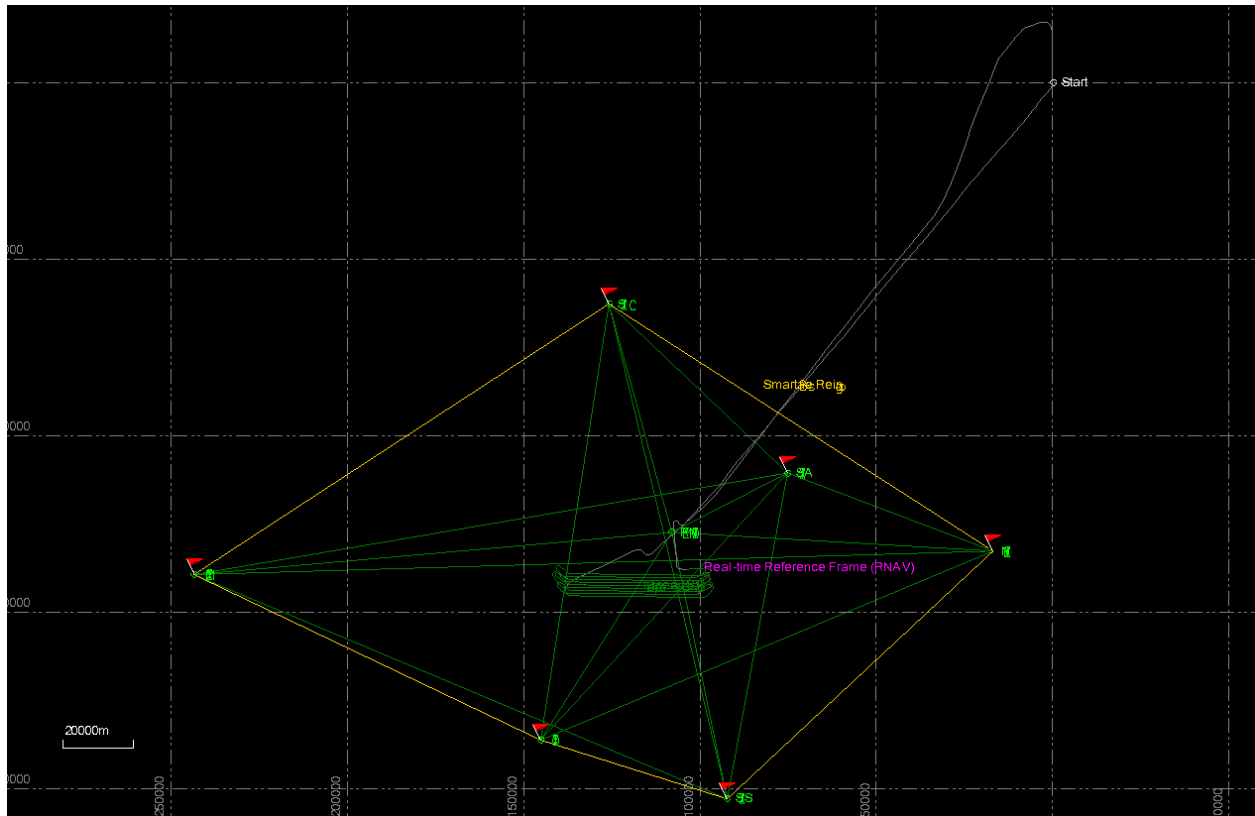
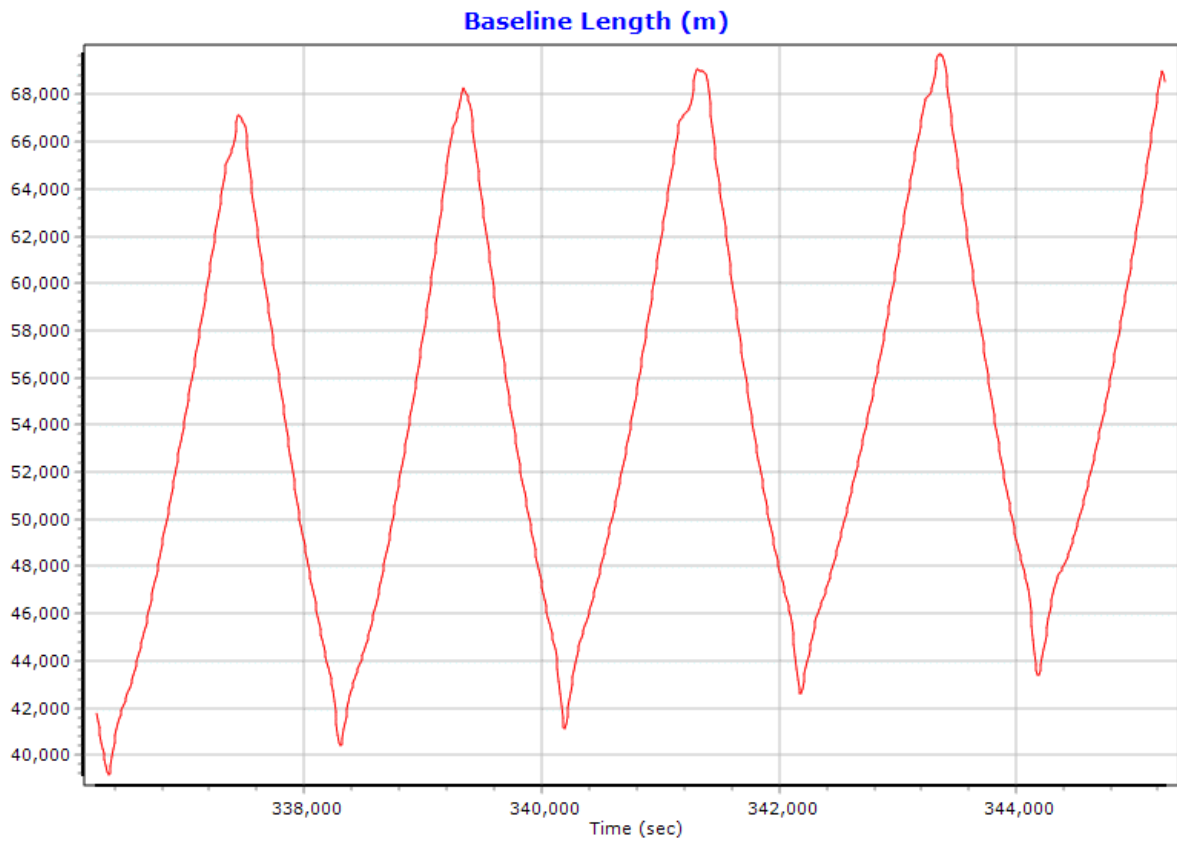


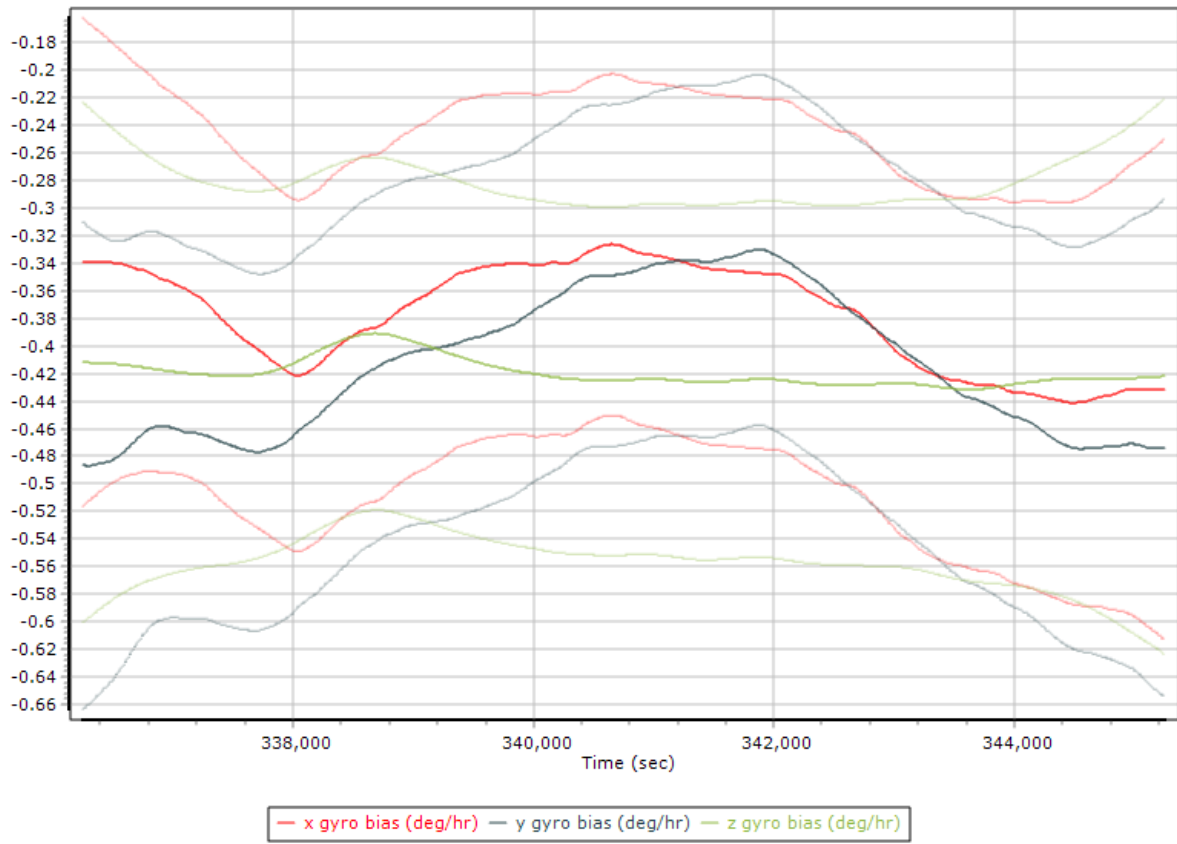
UNB18045A

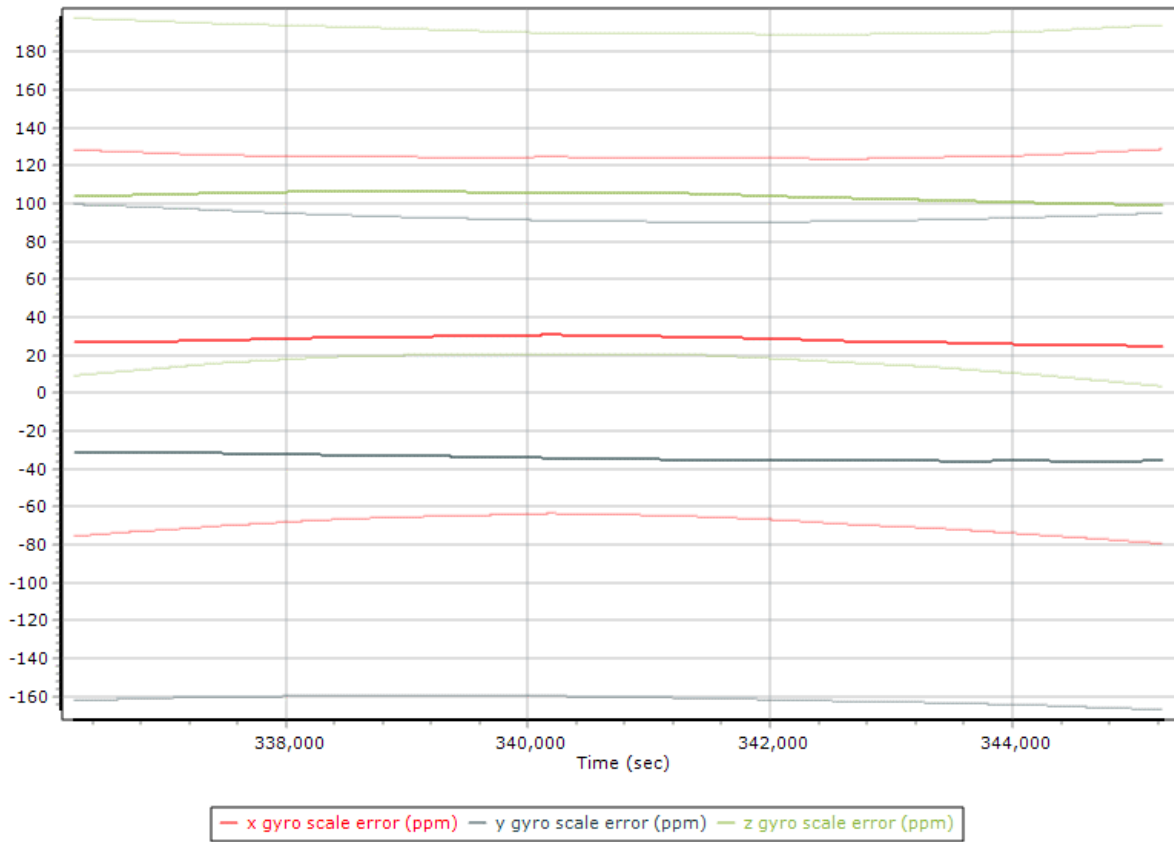












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

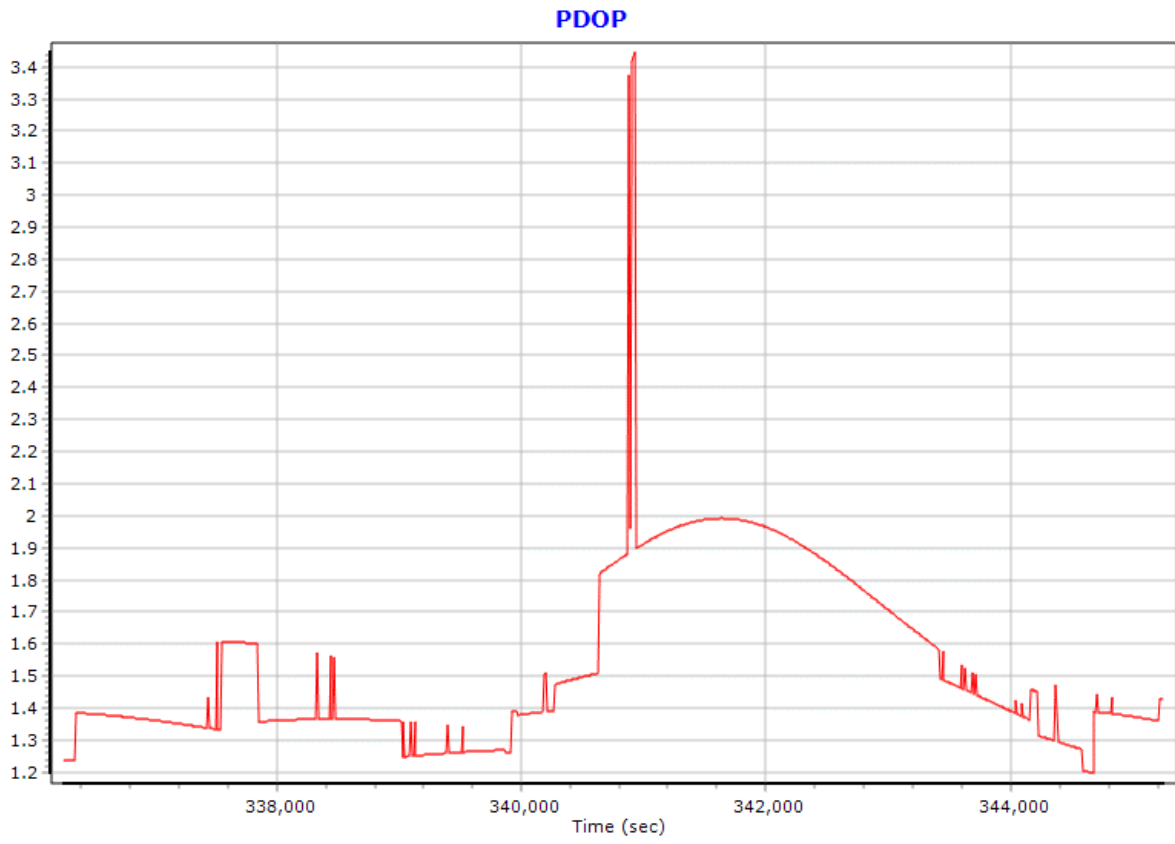
Aircraft to Reference Mounting Angles

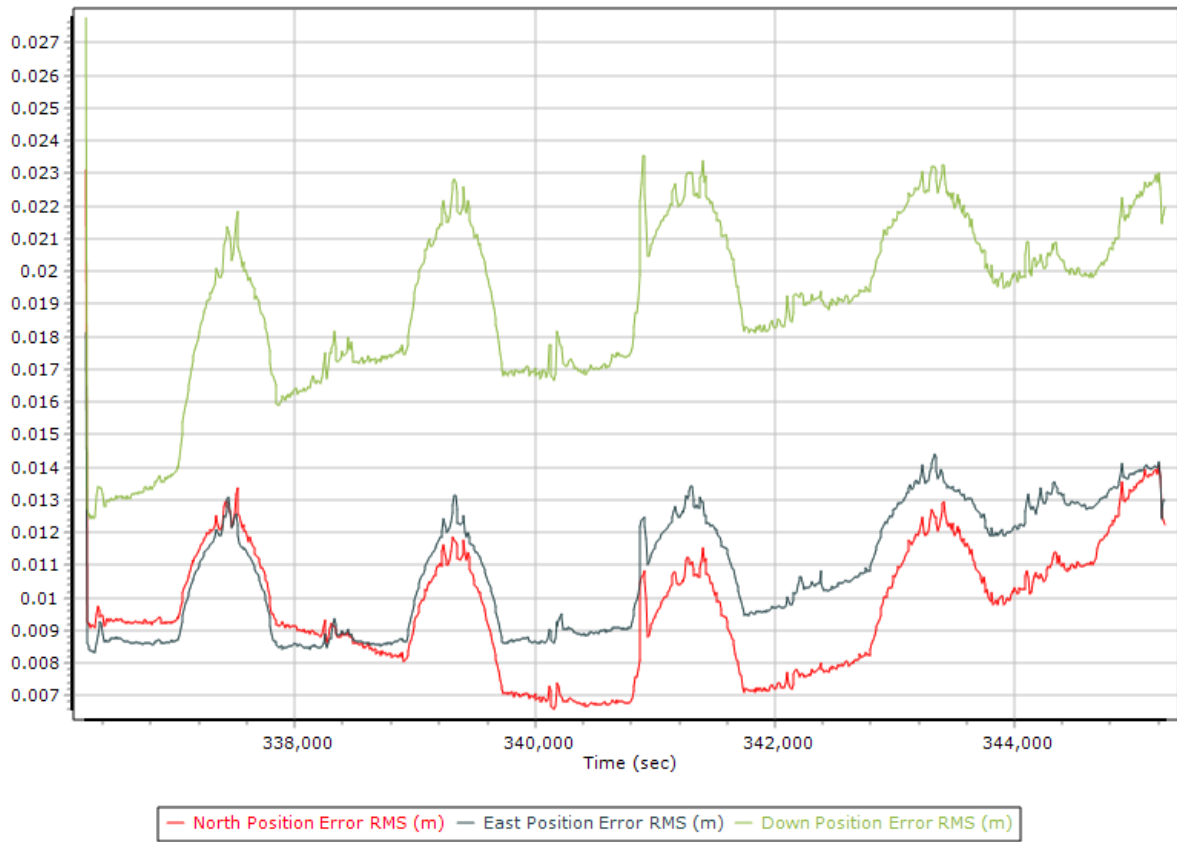
X:

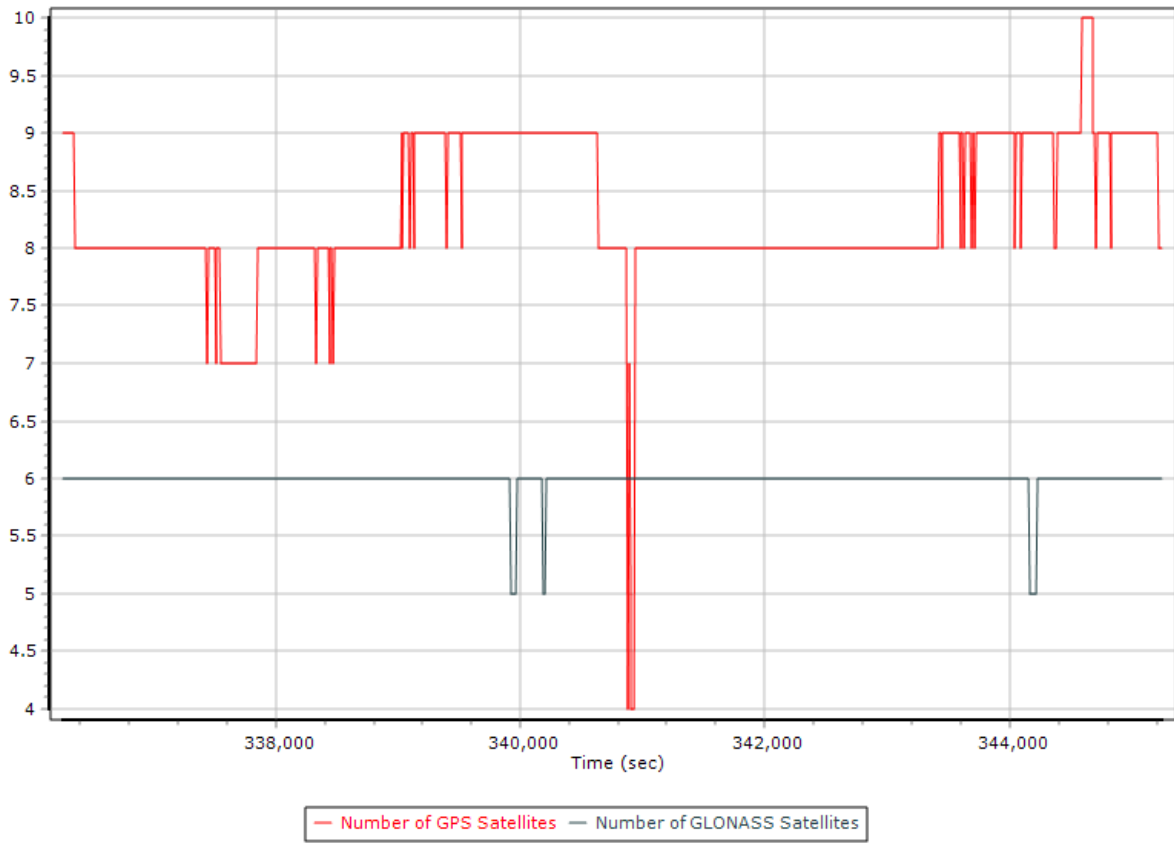
Y:

Z:

OK Cancel









Project Settings [X]

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

Timing

Start: 336253.983
 End: 345264.326

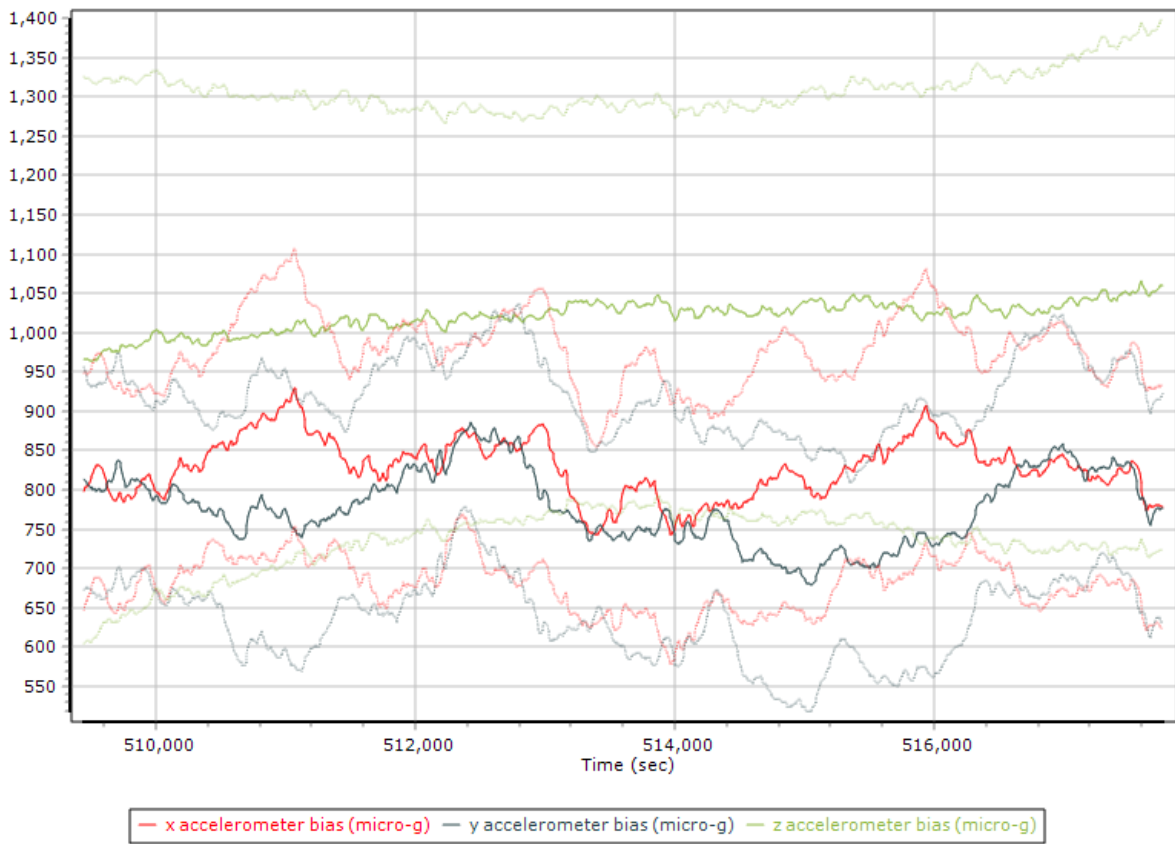
Entire time interval
 Seconds of start week

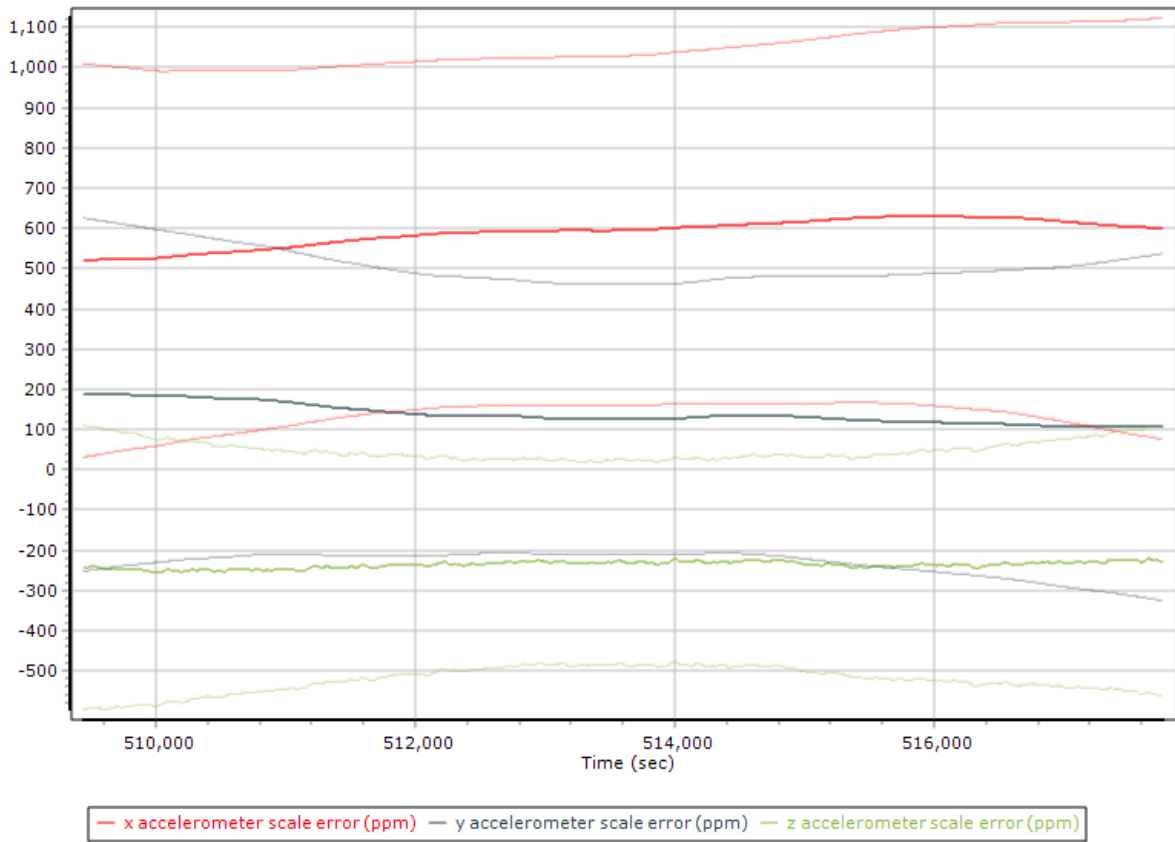
UTC Offset: 18.000

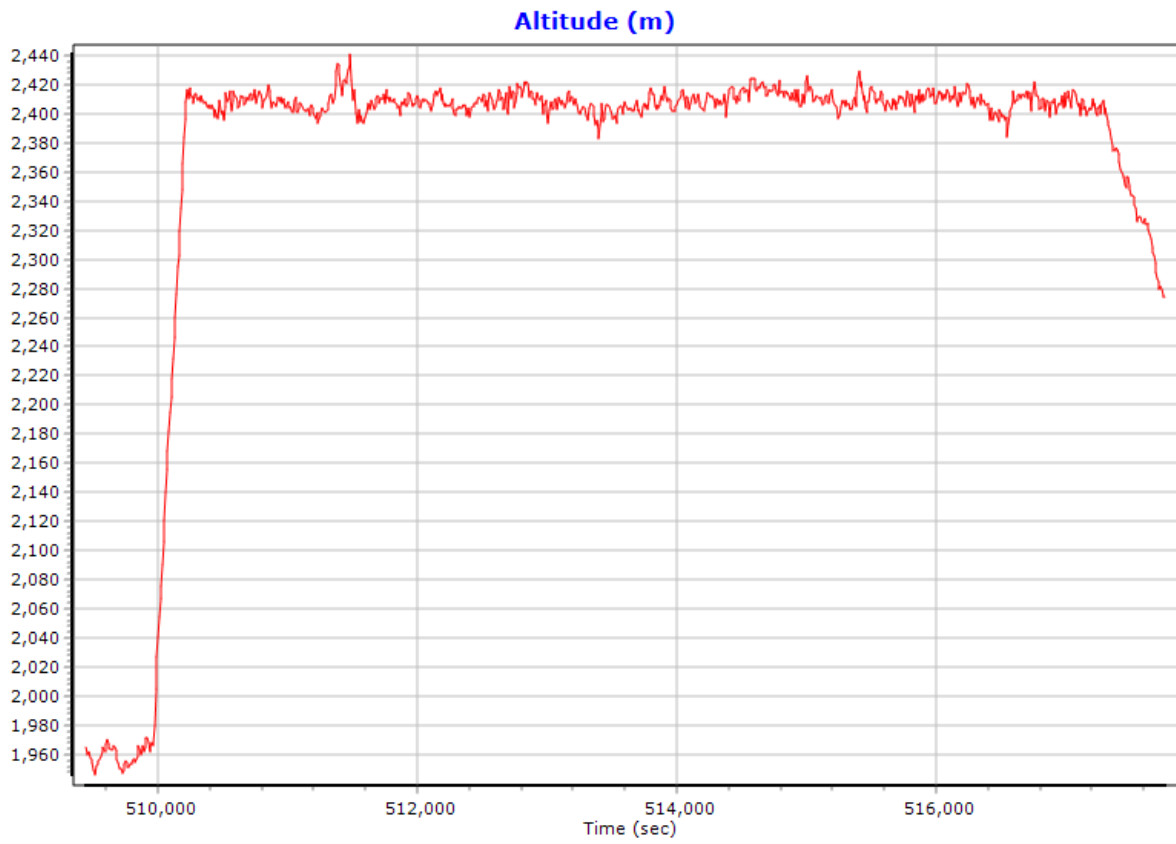
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

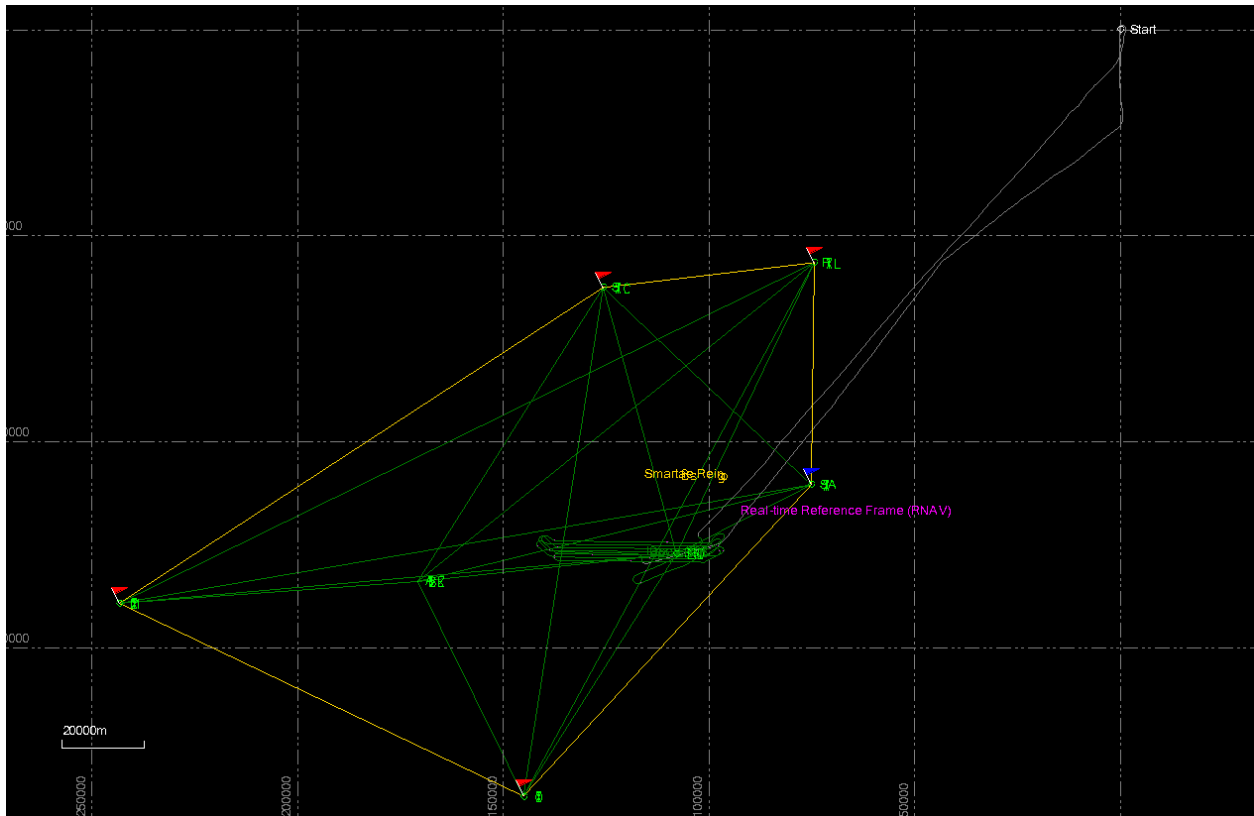
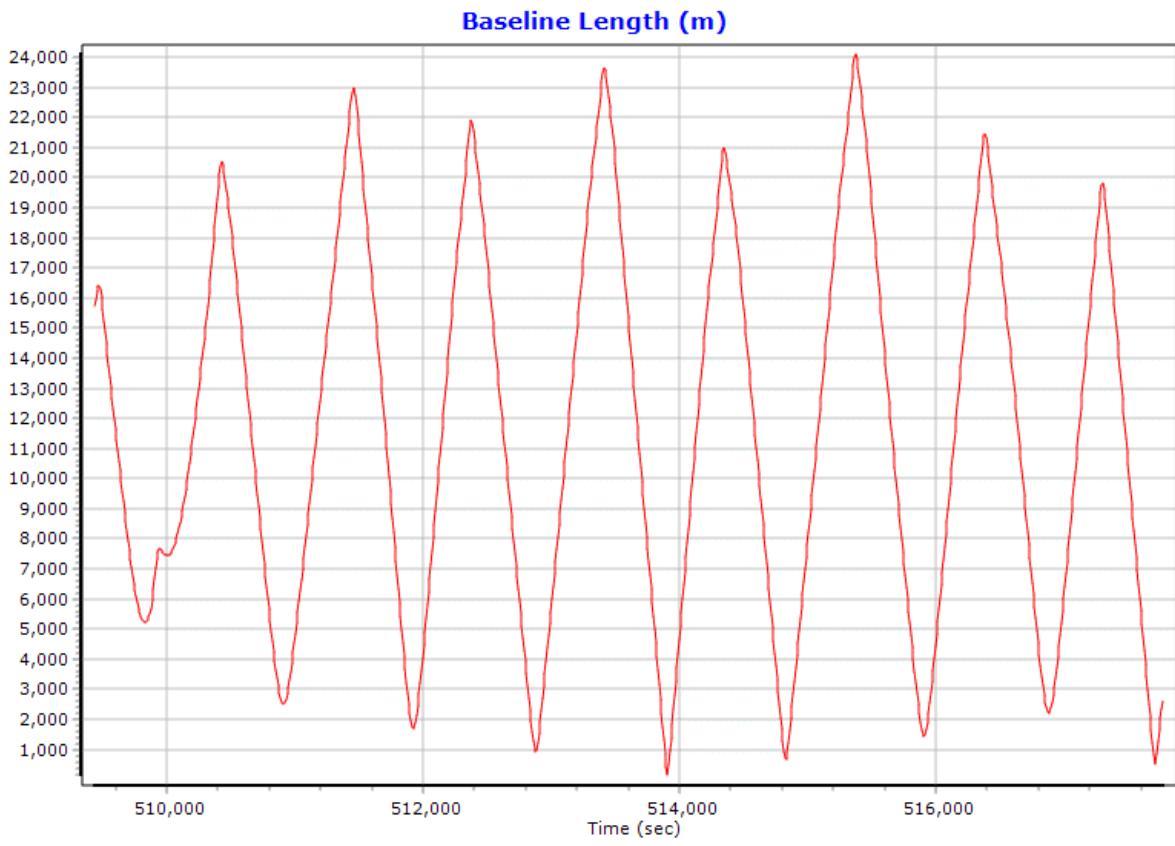
OK Cancel

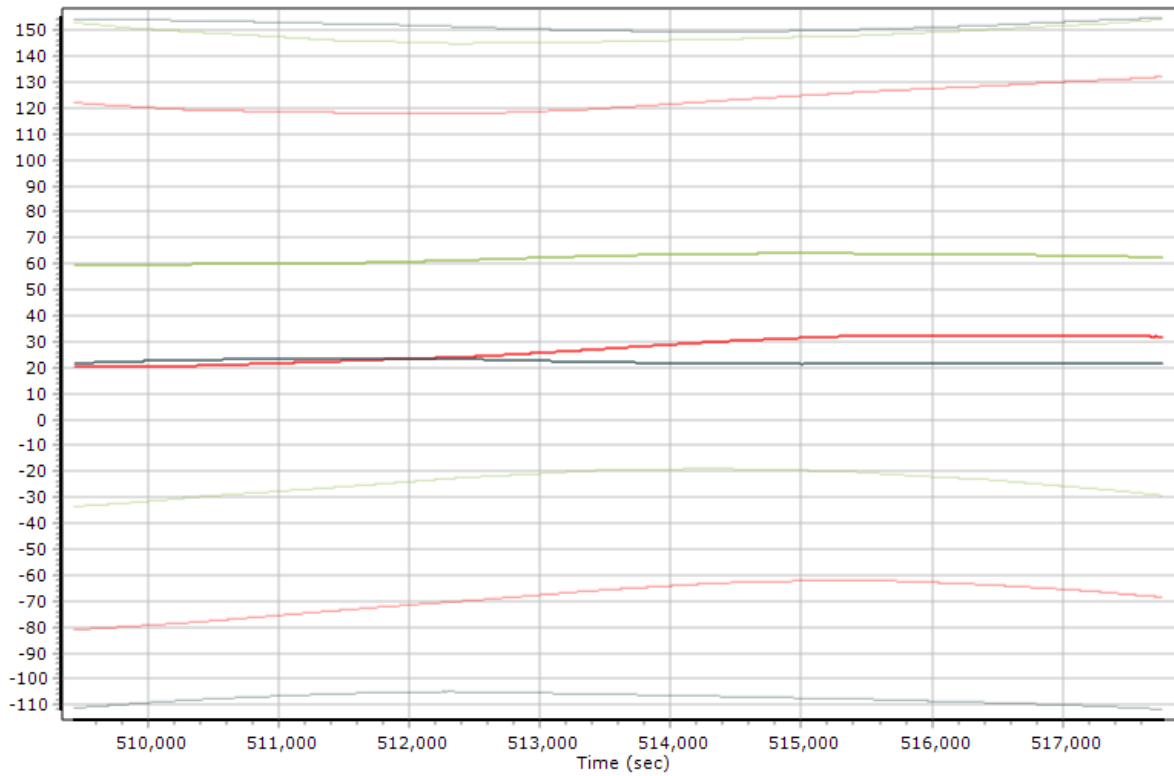
UNB18047A











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

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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

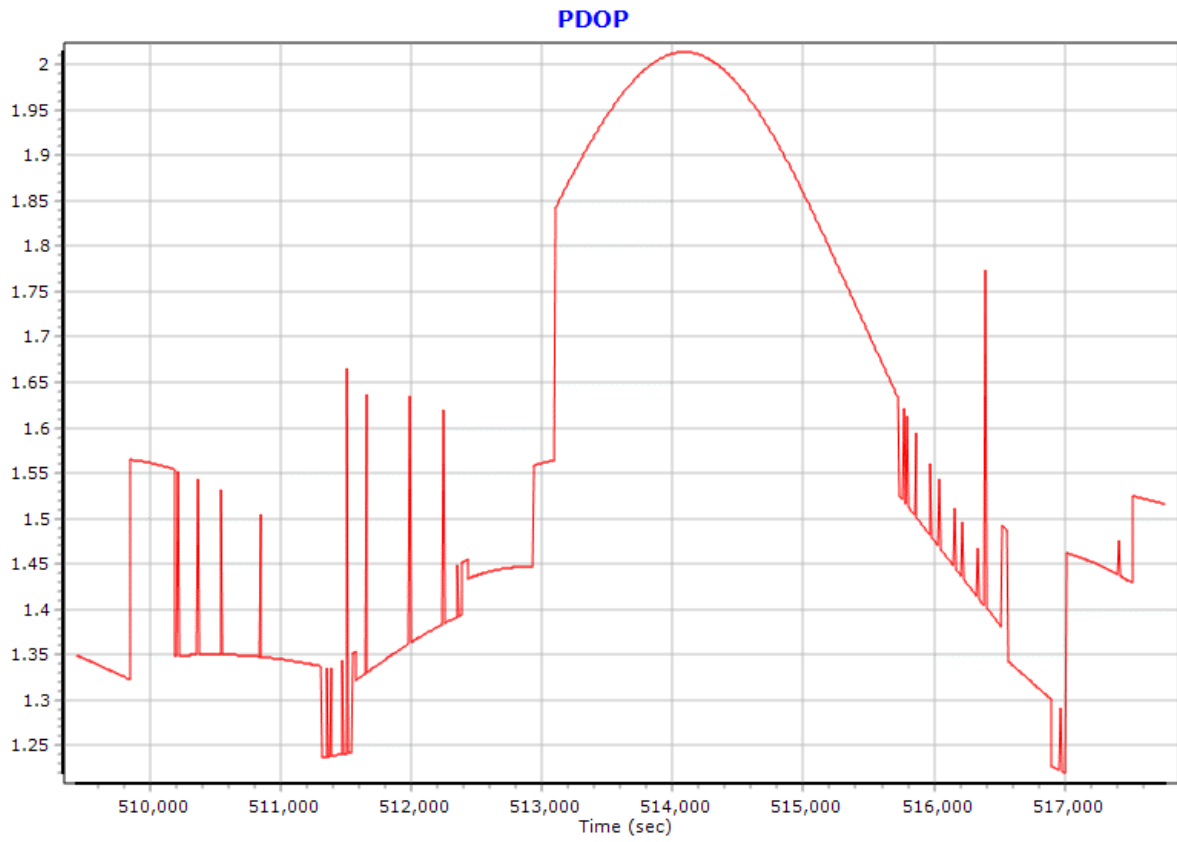
<3cm 10cm 50cm 1m 10m

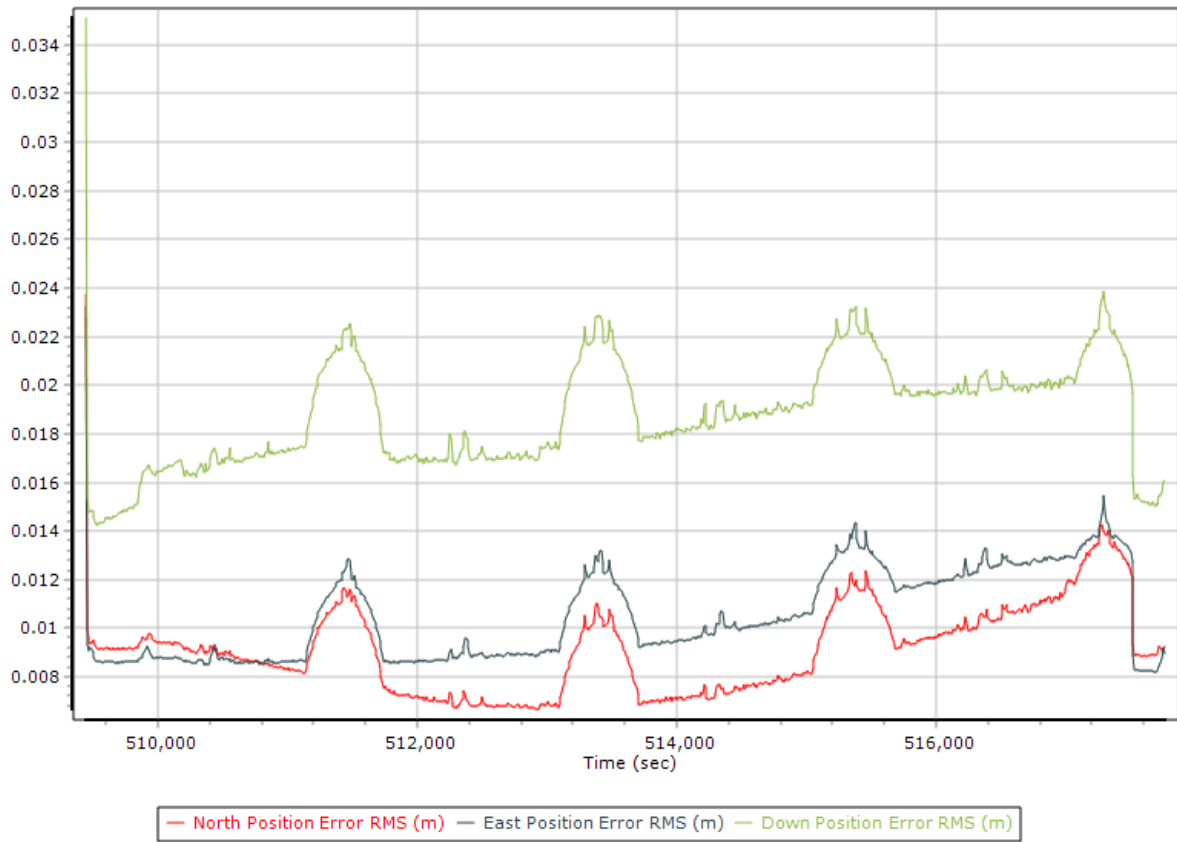
Aircraft to Reference Mounting Angles

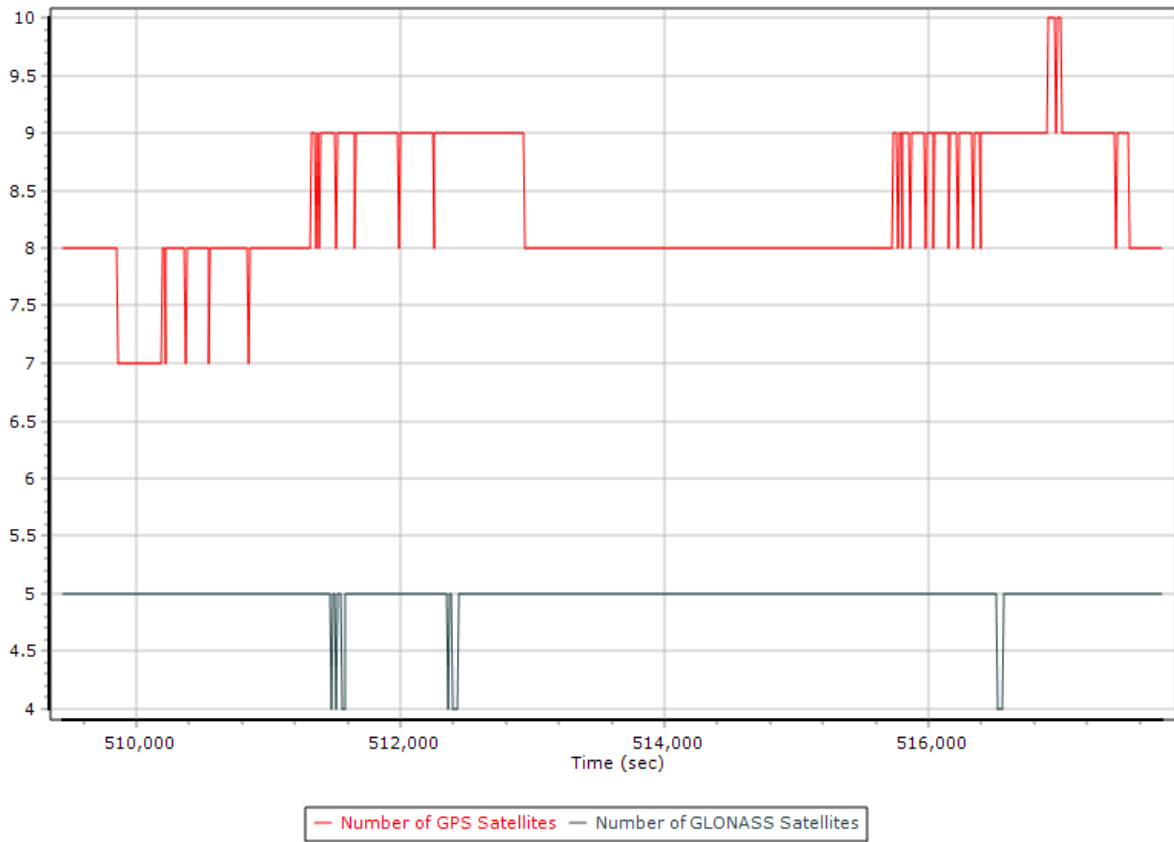
X:

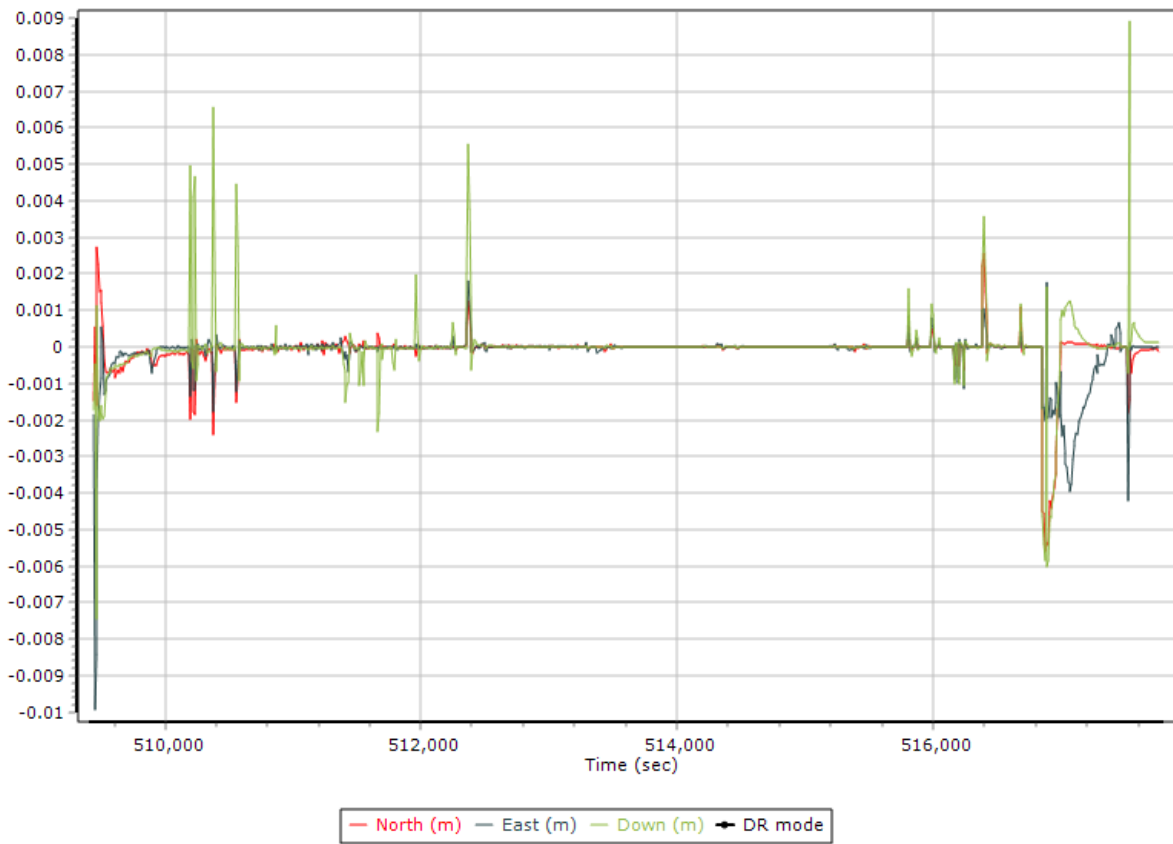
Y:

Z:









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: 509438.183
End: 517778.497

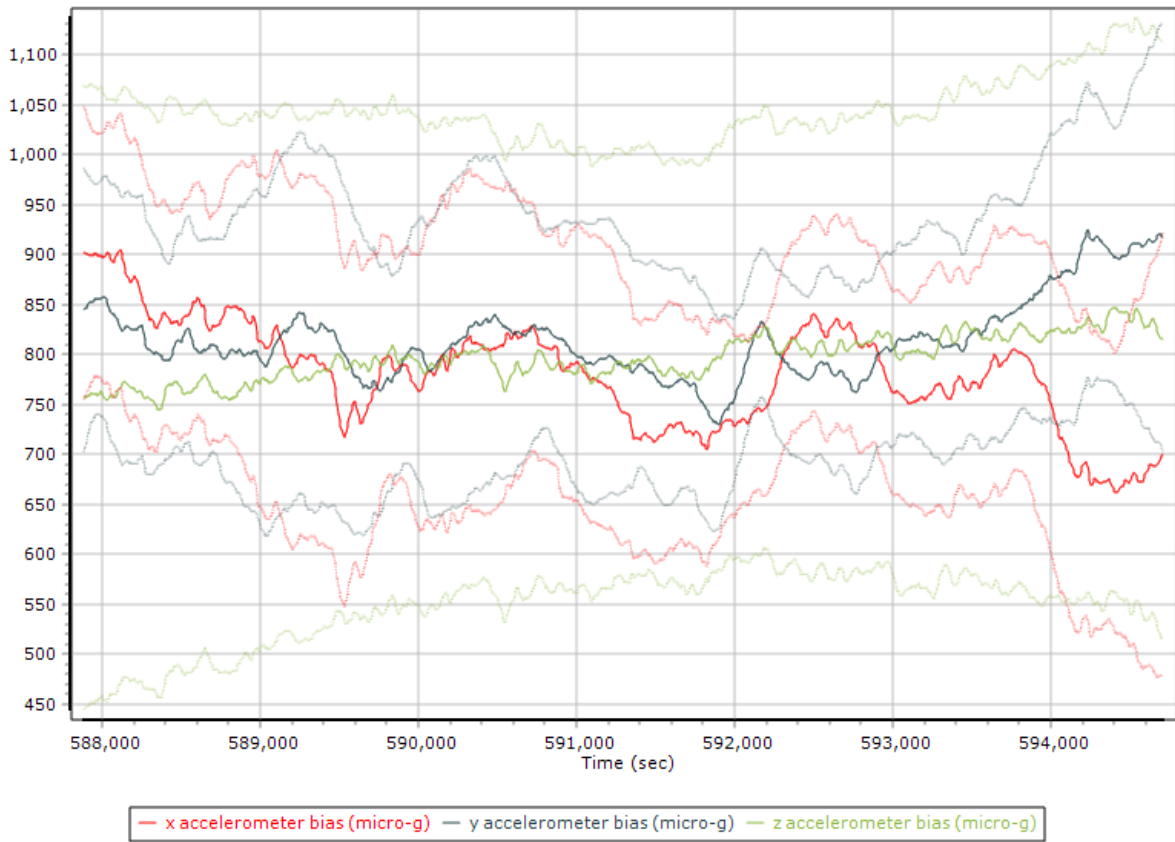
Entire time interval
 Seconds of start week

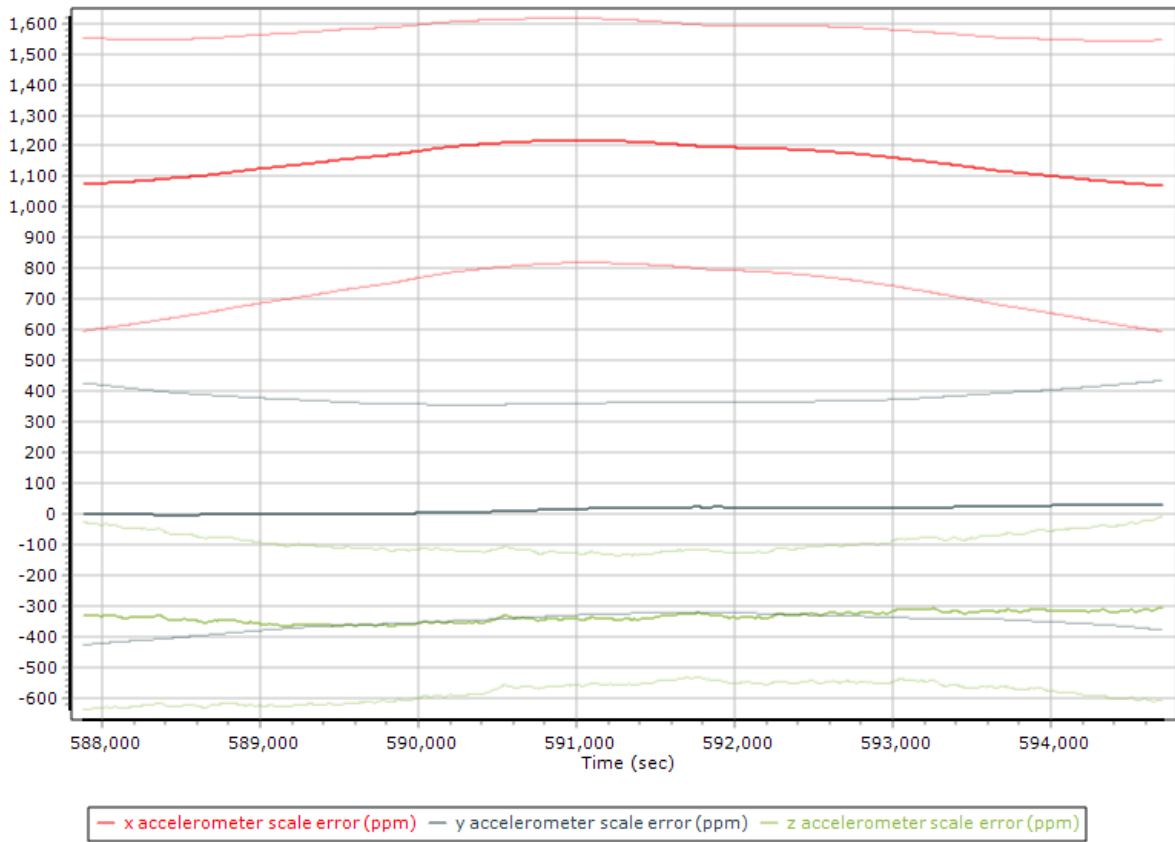
UTC Offset: 18.000

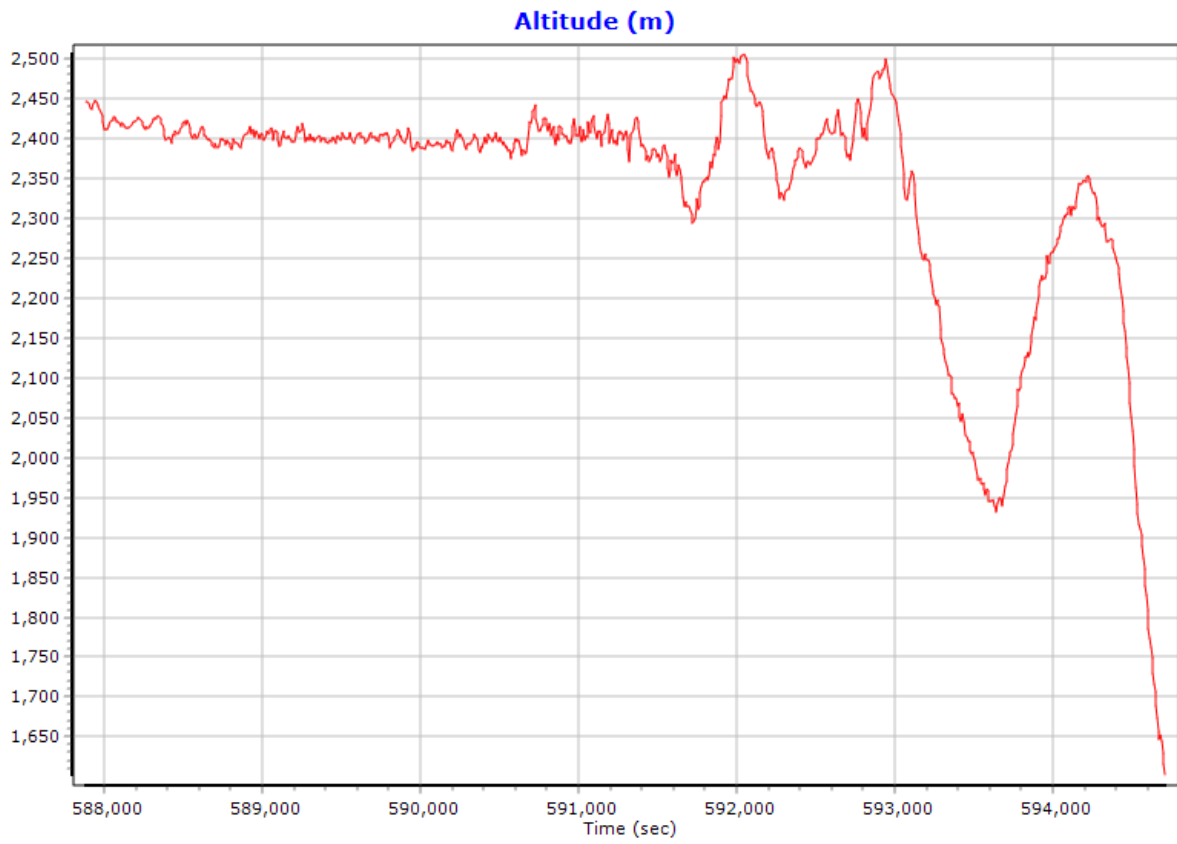
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

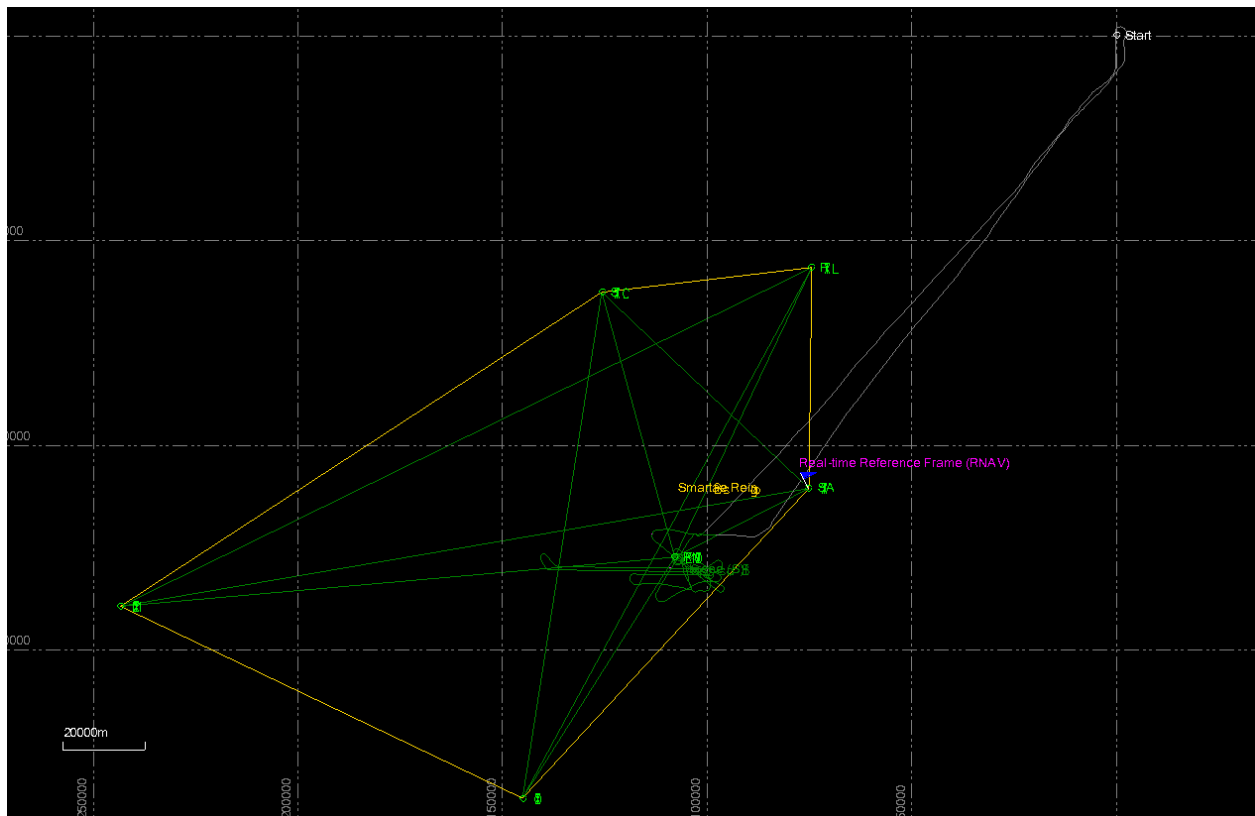
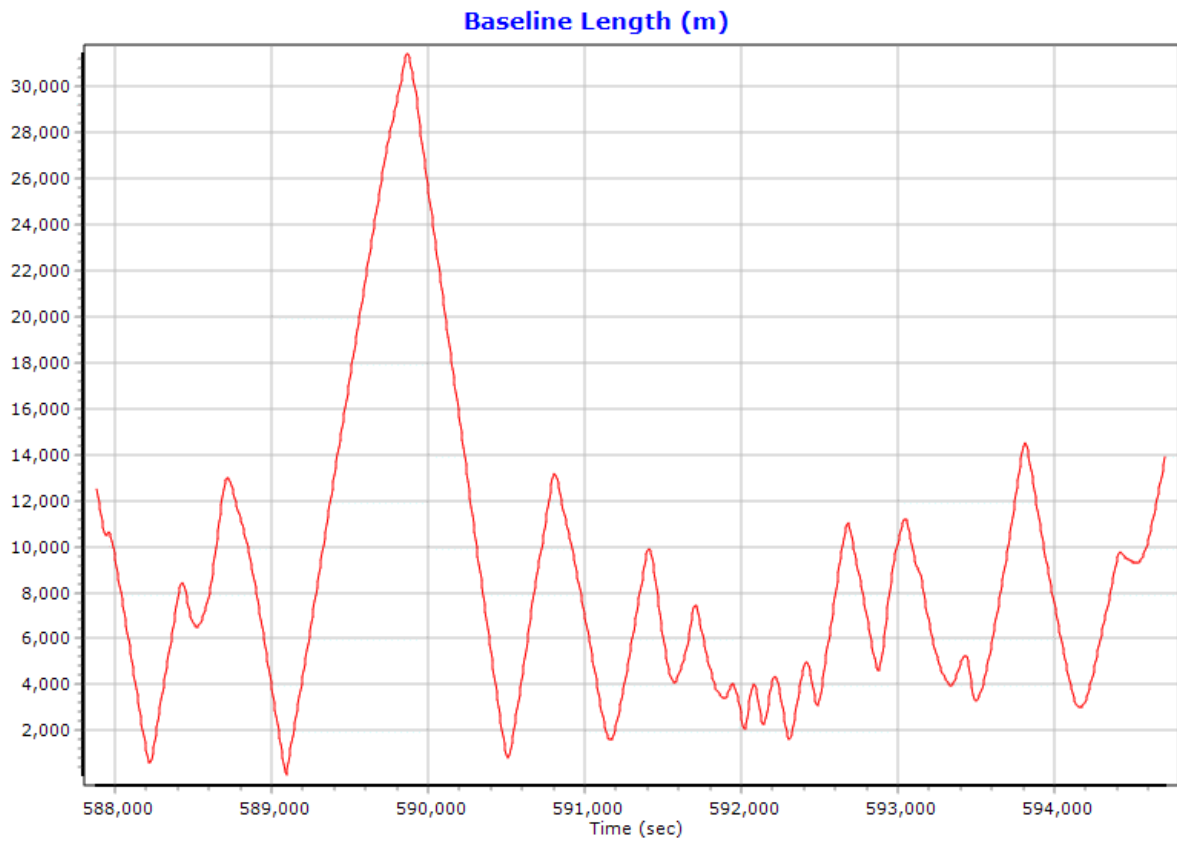
OK Cancel

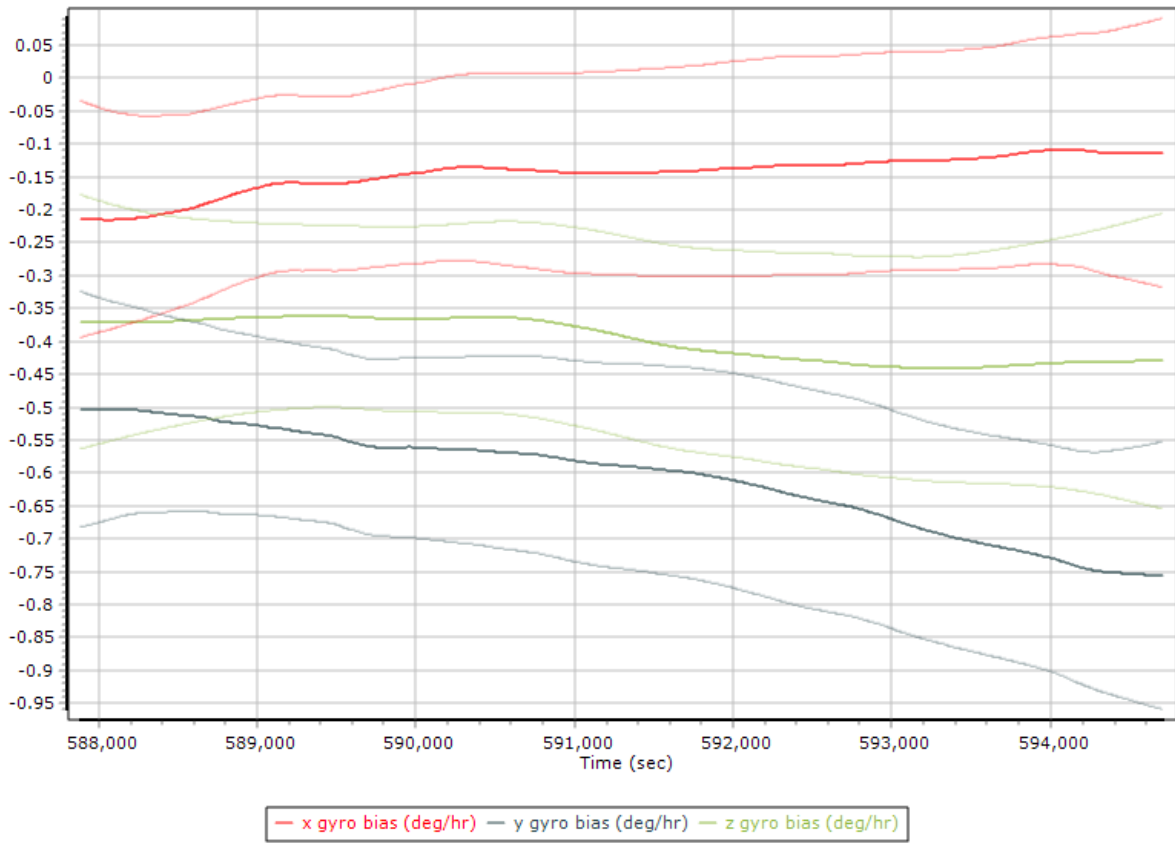
UNB18048A

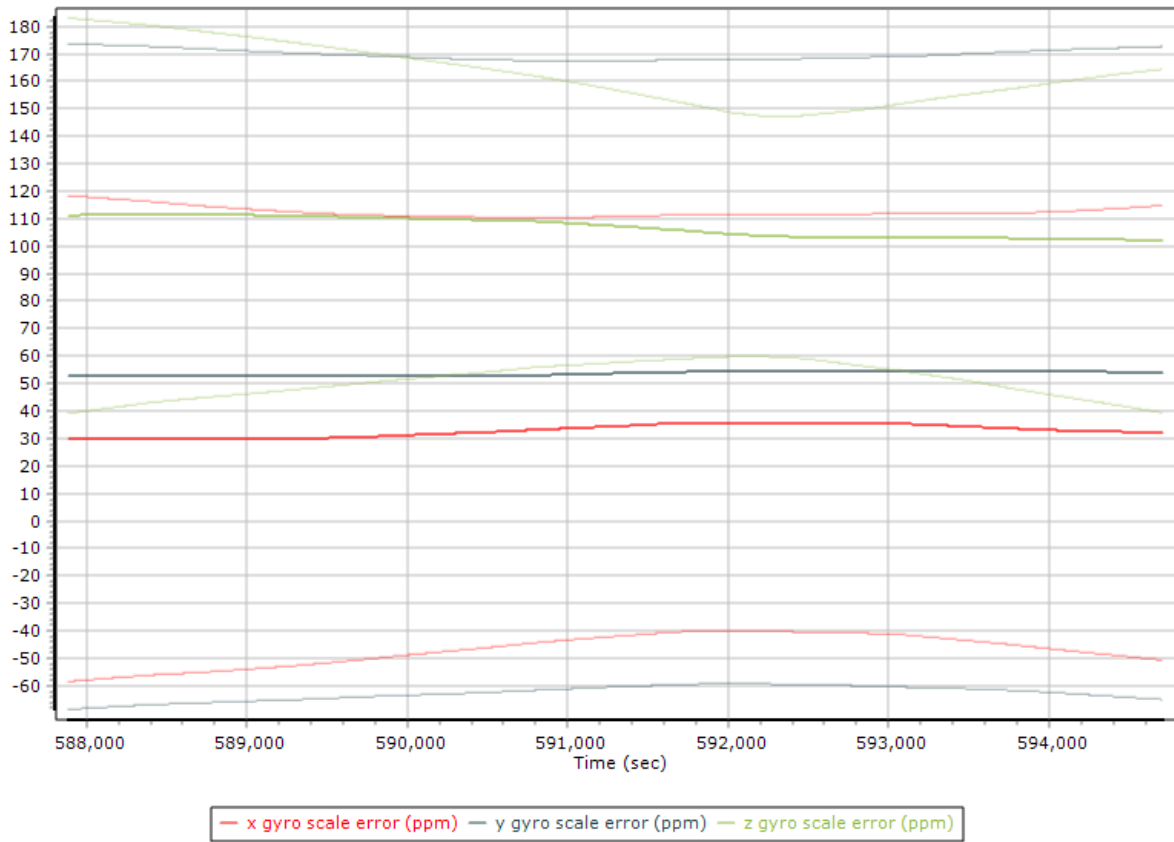












Project Settings [X]

- General Information
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 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

Reference to IMU Lever Arm

X	0.034 m
Y	0.018 m
Z	-0.155 m

Reference to IMU Mounting Angles

X	0.000 deg
Y	0.000 deg
Z	0.000 deg

Reference to Primary GNSS Lever Arm

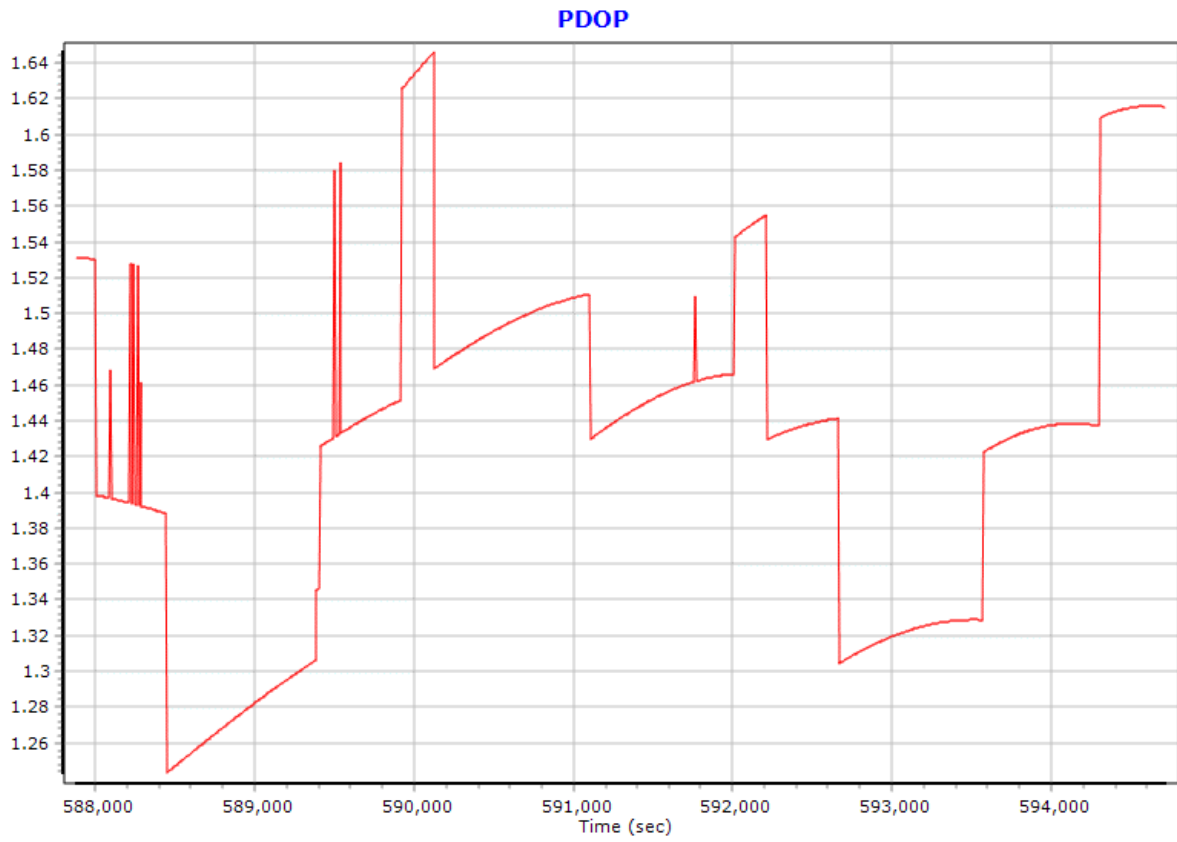
X	-0.105 m
Y	-0.052 m
Z	-0.964 m

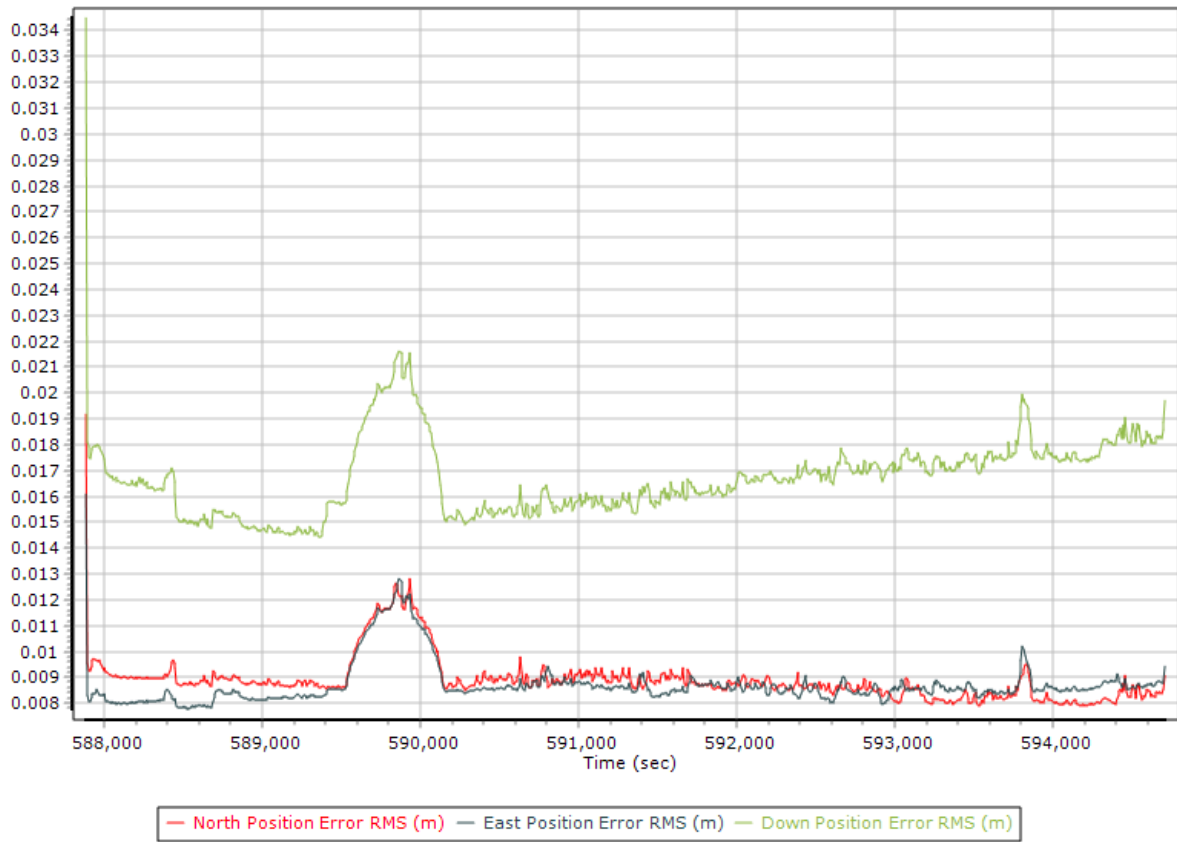
Aircraft to Reference Mounting Angles

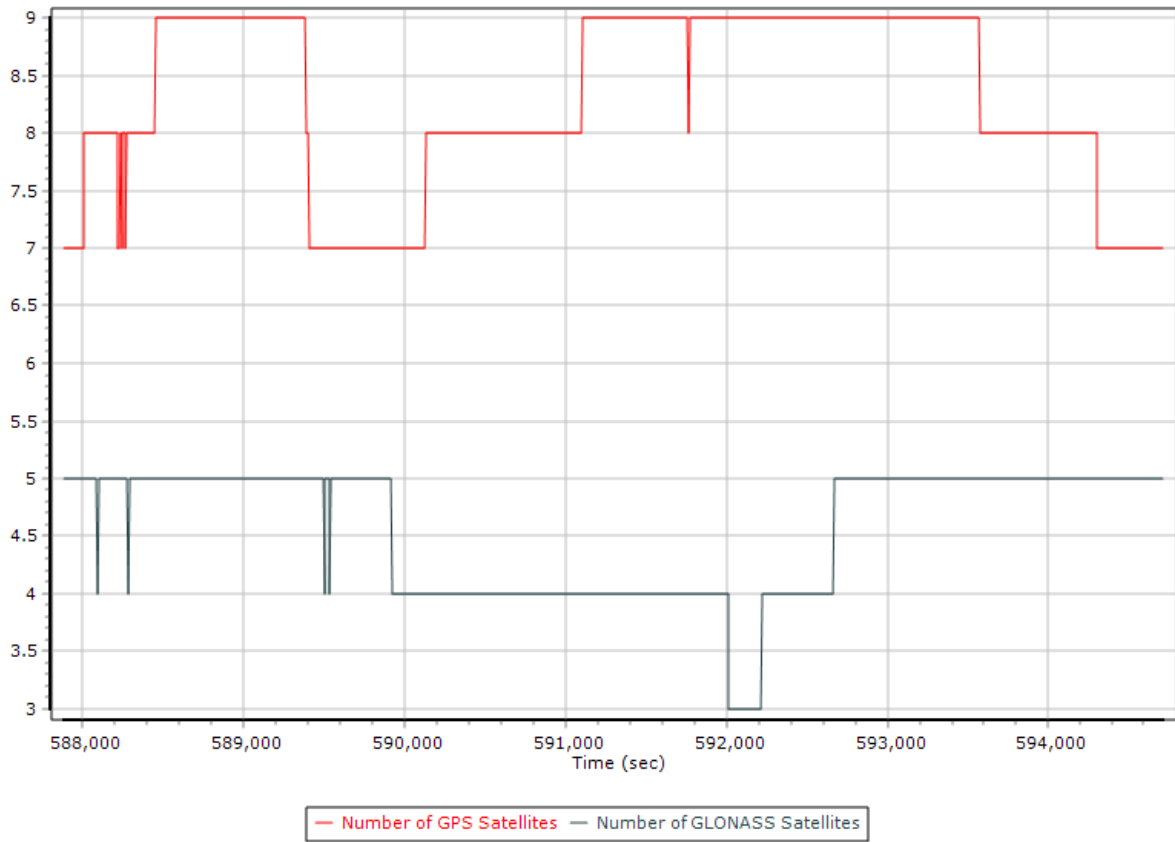
X	0.000 deg
Y	0.000 deg
Z	0.000 deg

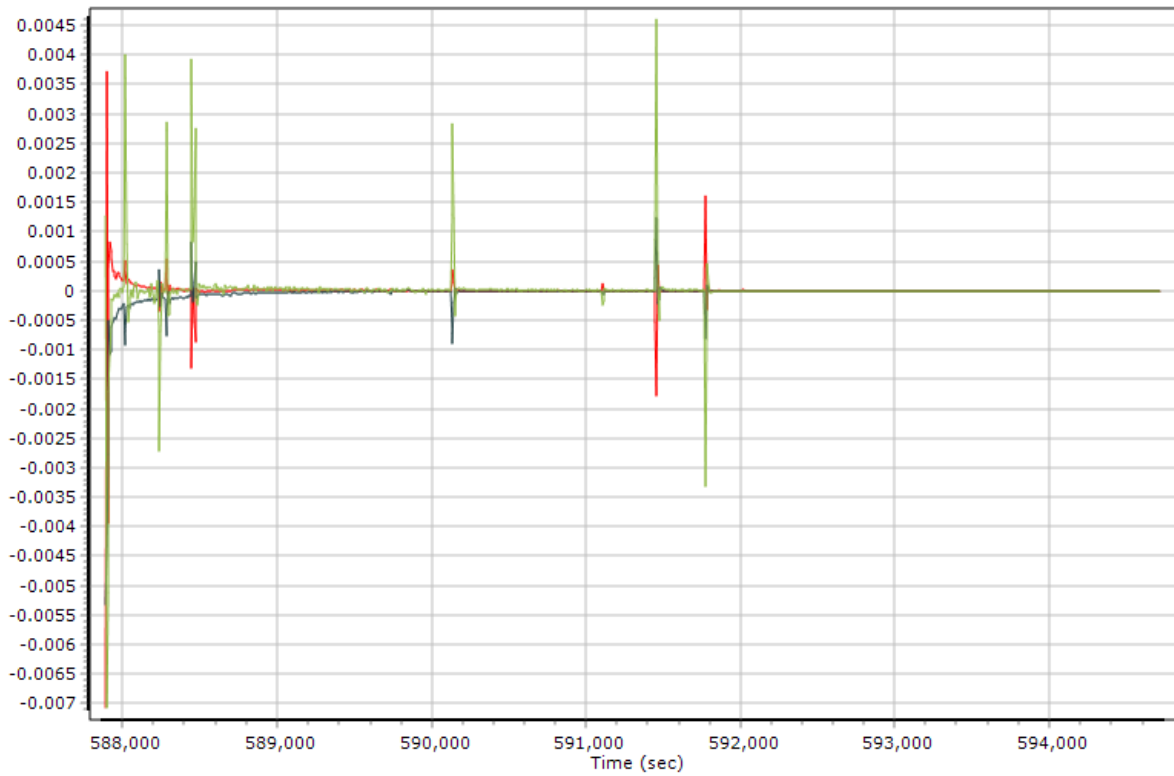
Standard Deviation: [Dropdown arrow] <3cm 10cm 50cm 1m 10m

OK Cancel









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

Project Settings

- General Information
- Units
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 - Timing
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 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LIDAR
- SAR

Timing

Start: 587882.920
 End: 594717.171

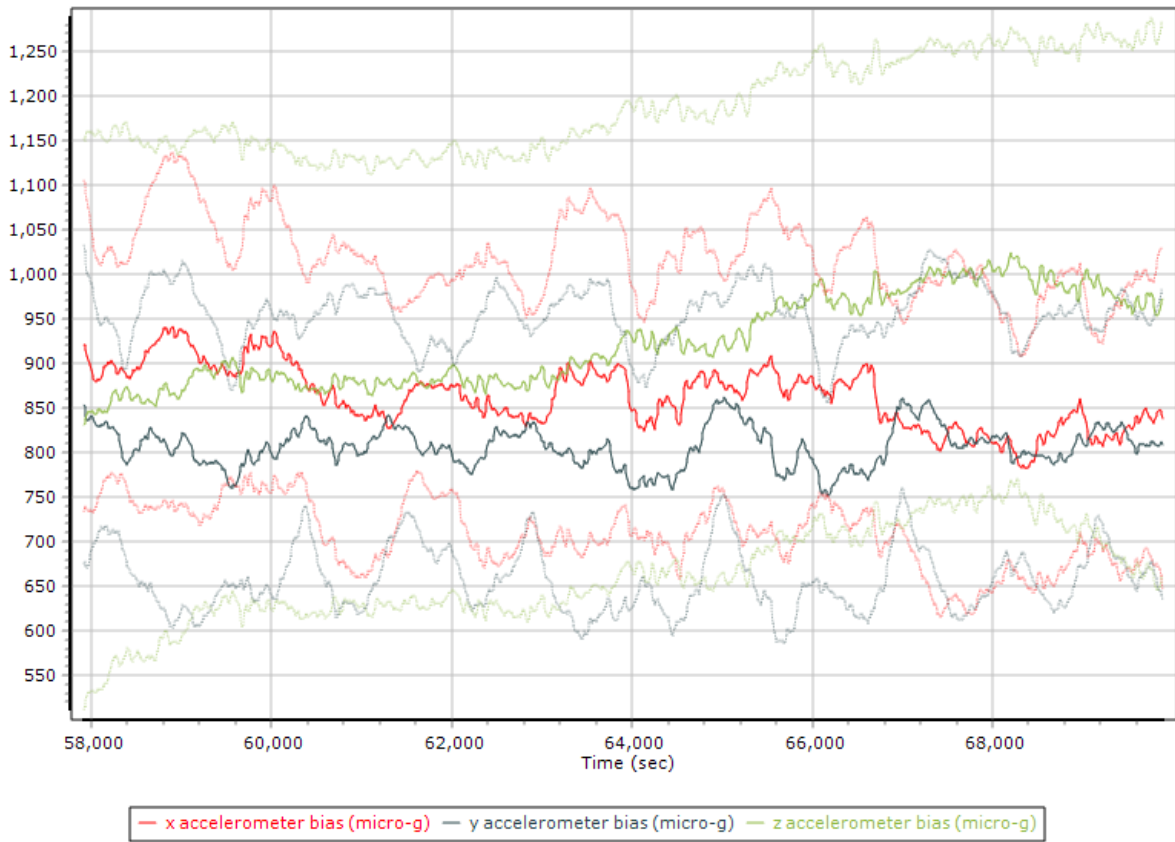
Entire time interval
 Seconds of start week

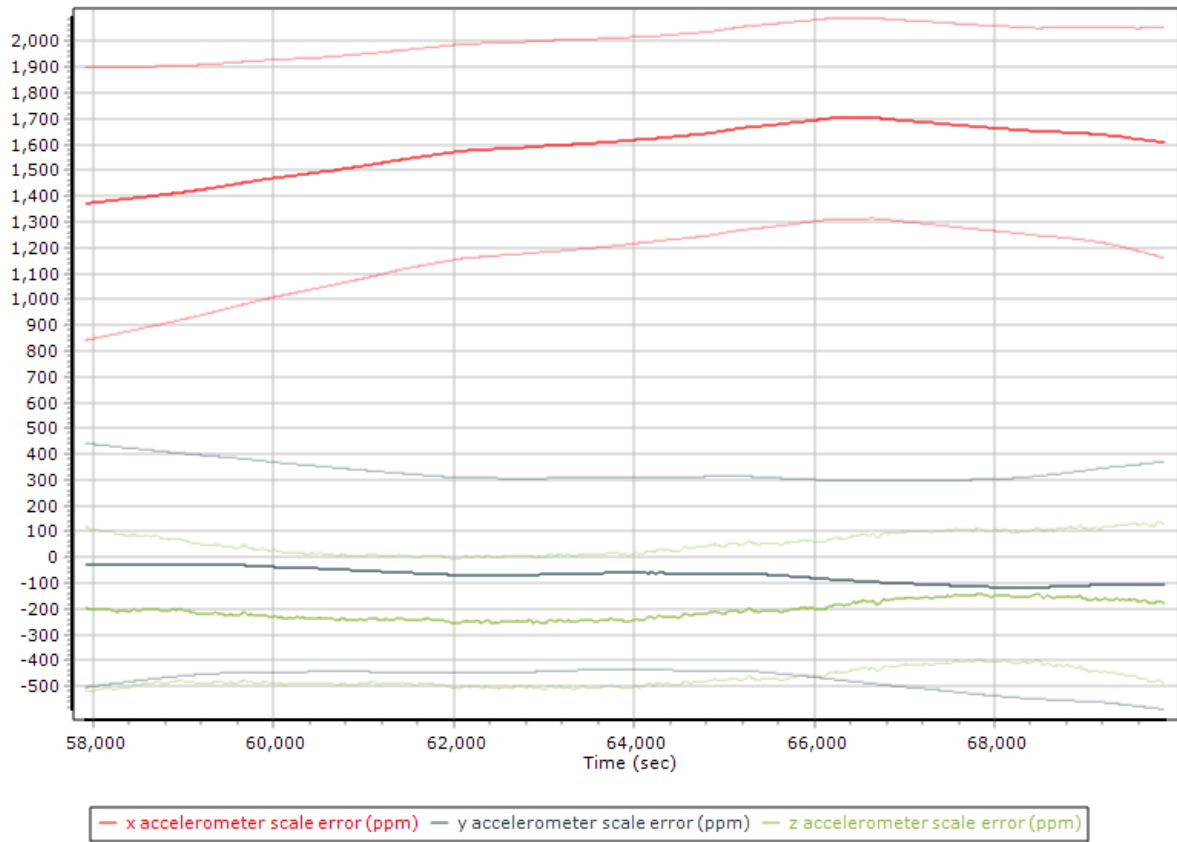
UTC Offset: 18.000

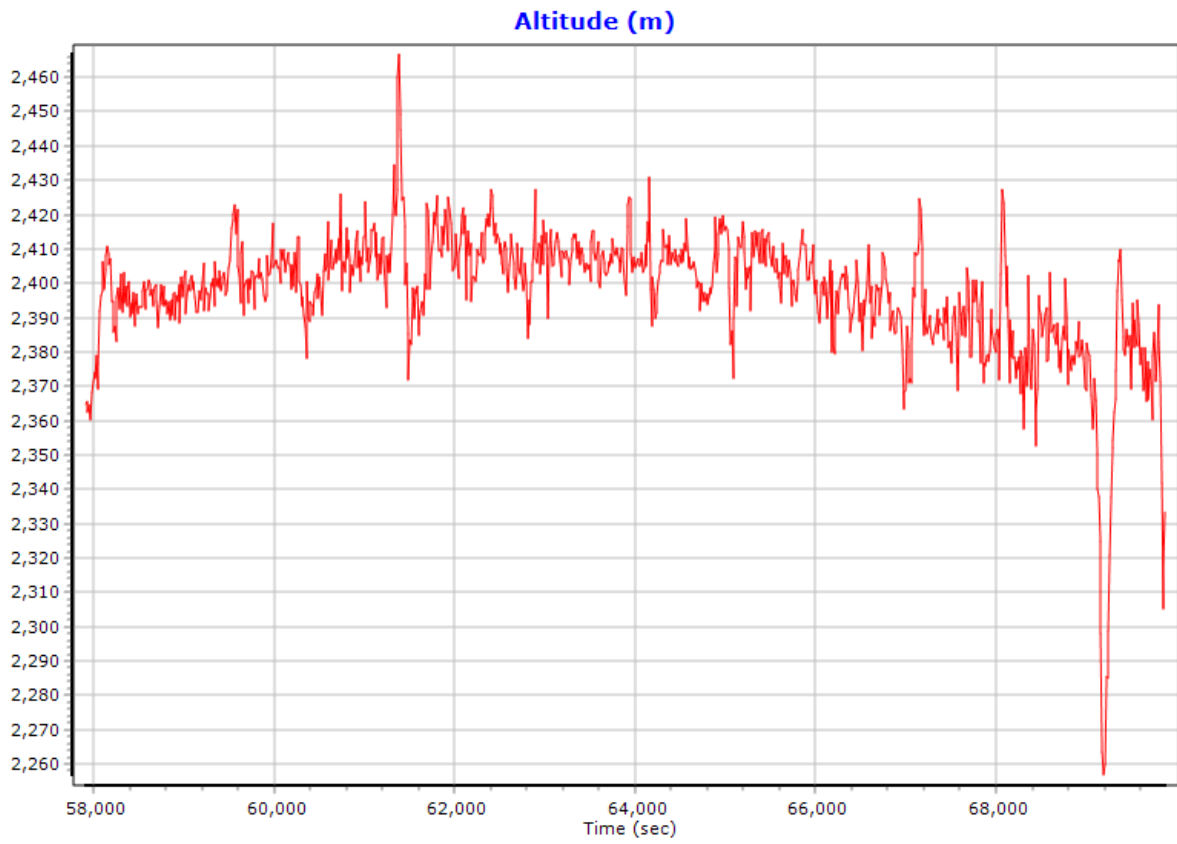
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

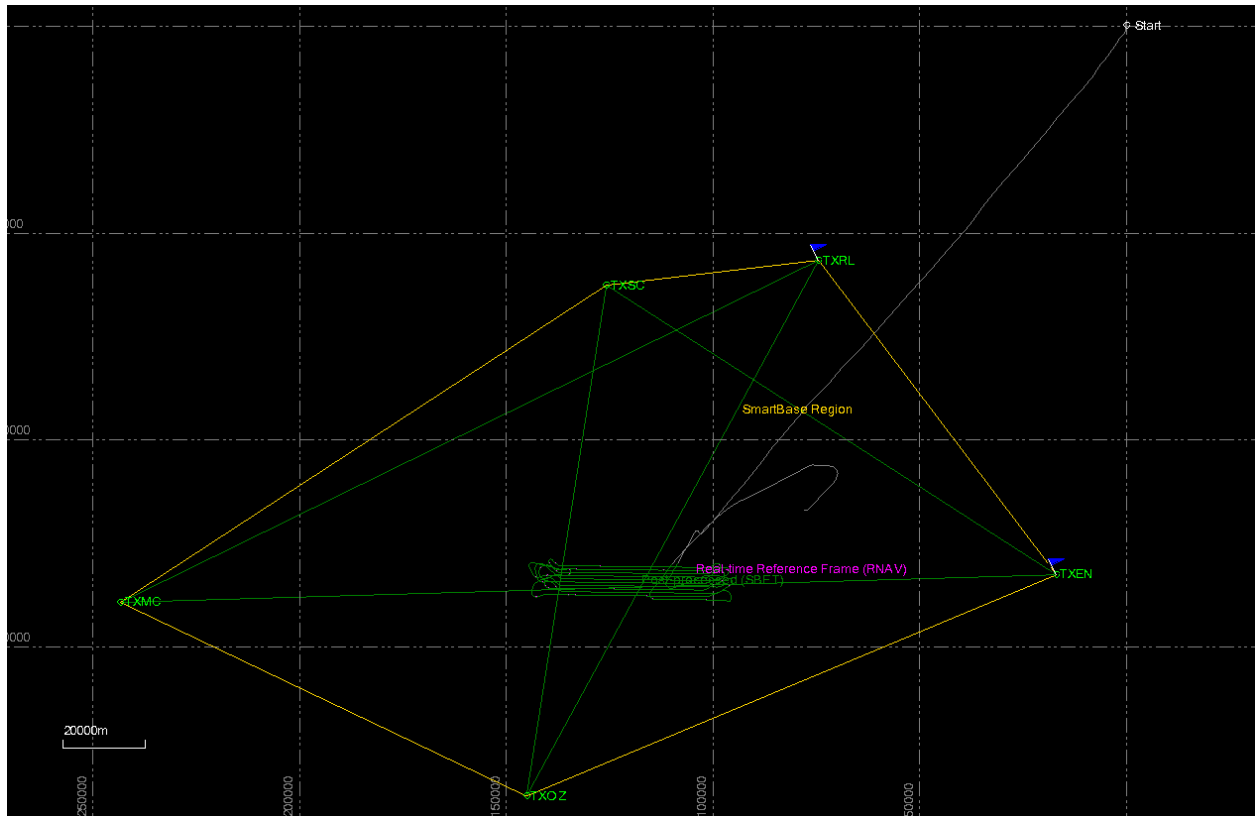
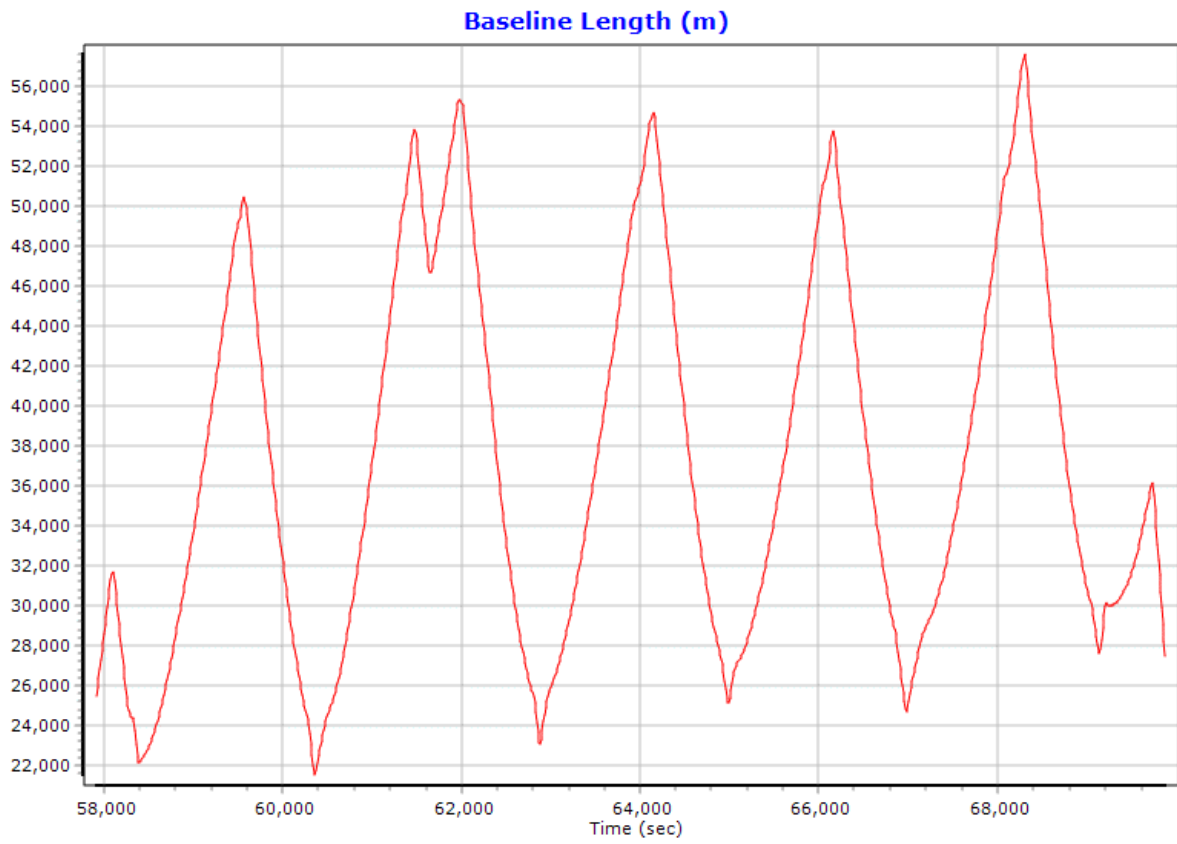
OK Cancel

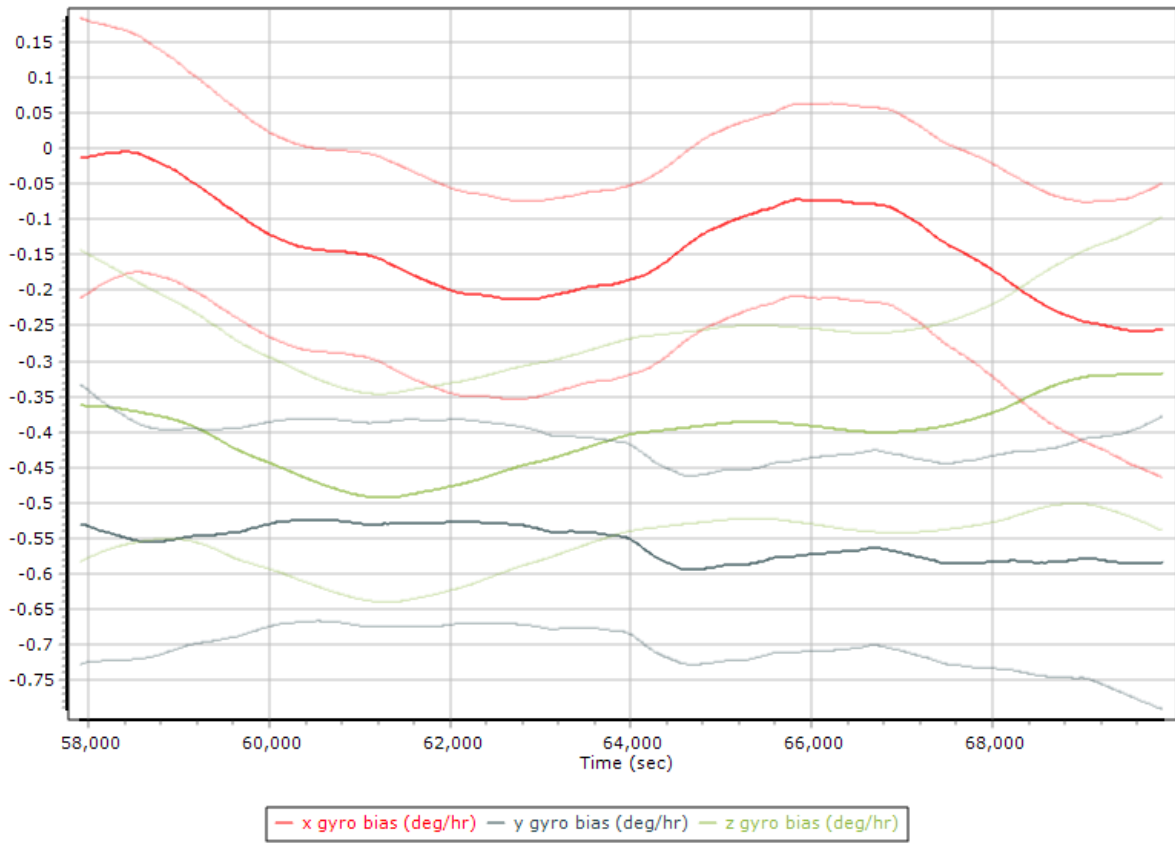
UNB18056A

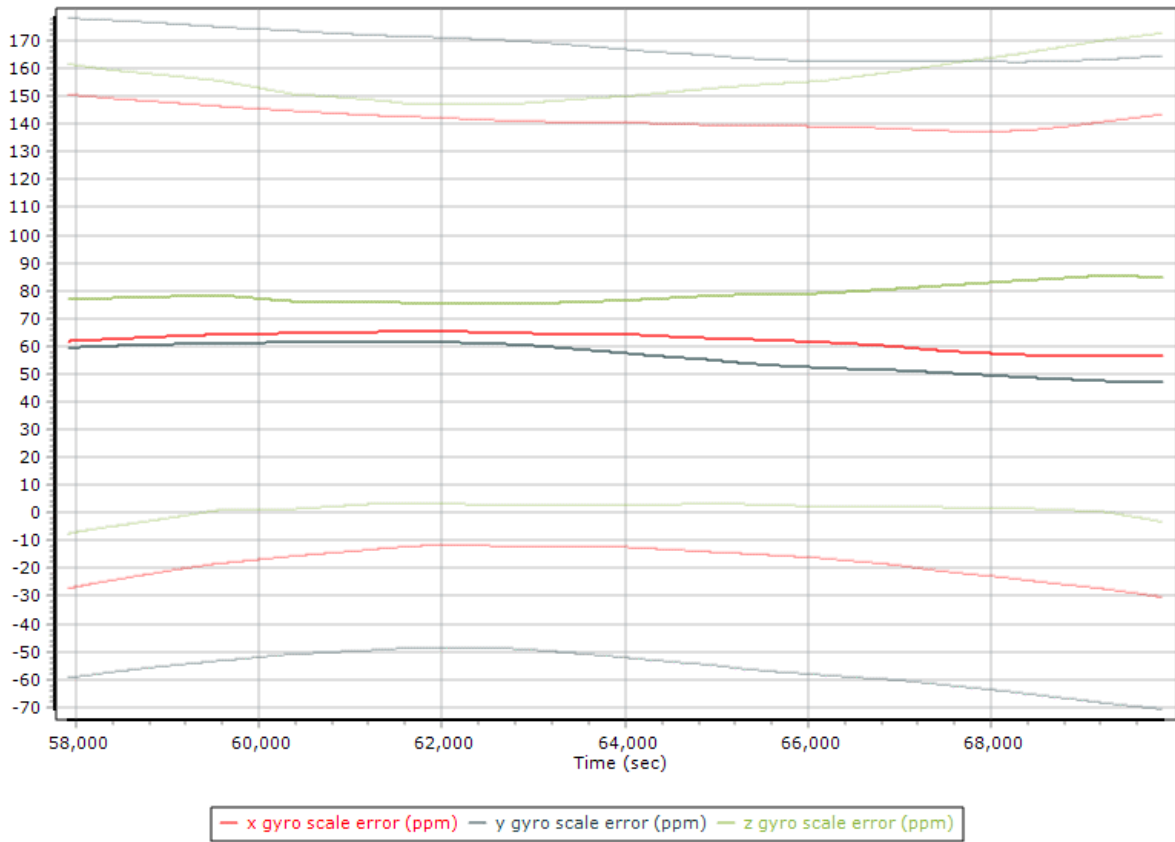












Project Settings ✕

- General Information
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 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LIDAR
- SAR

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

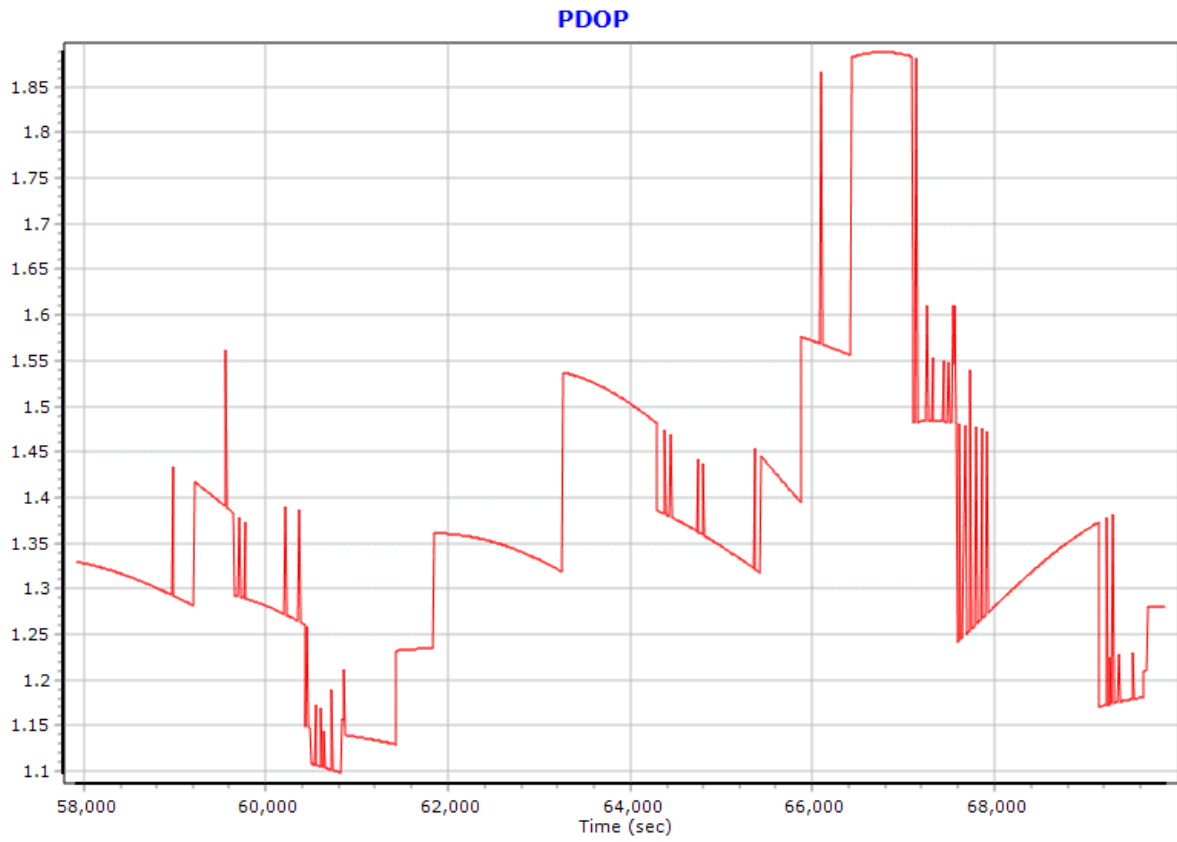
<3cm 10cm 50cm 1m 10m

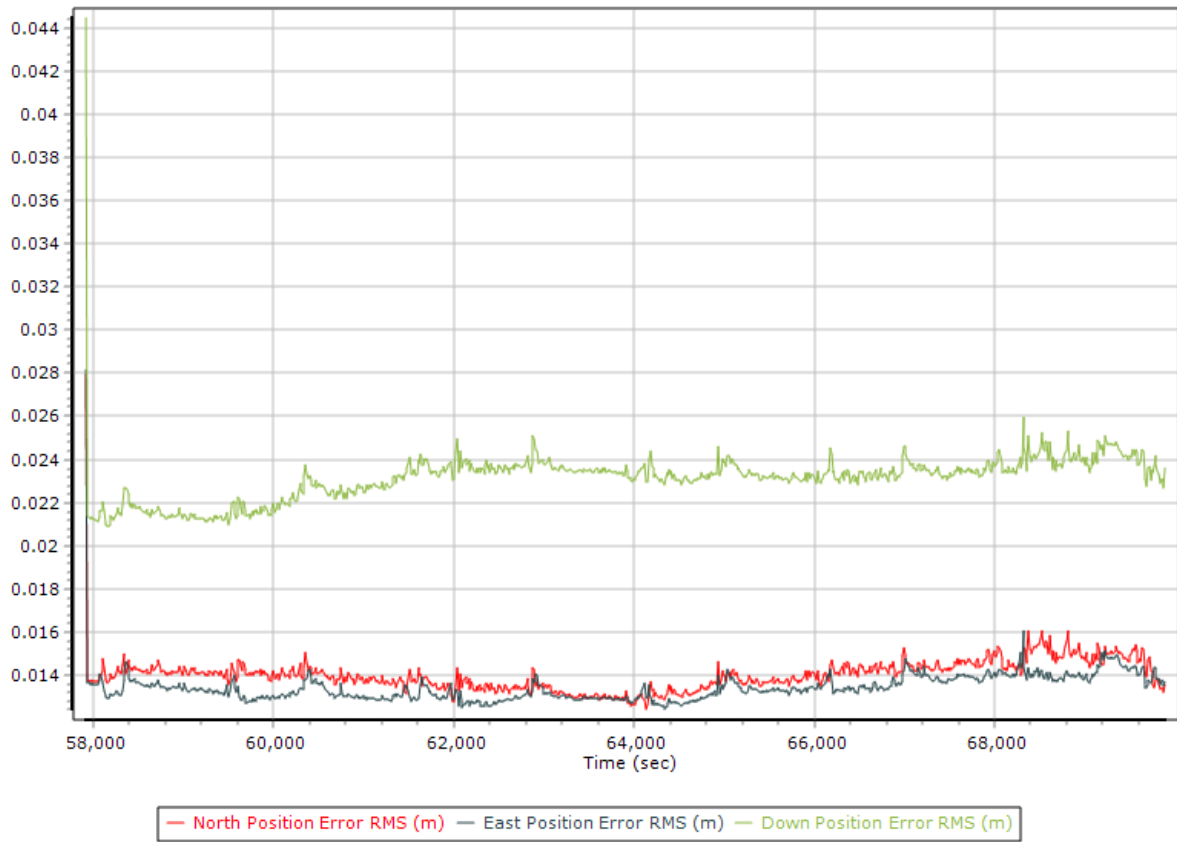
Aircraft to Reference Mounting Angles

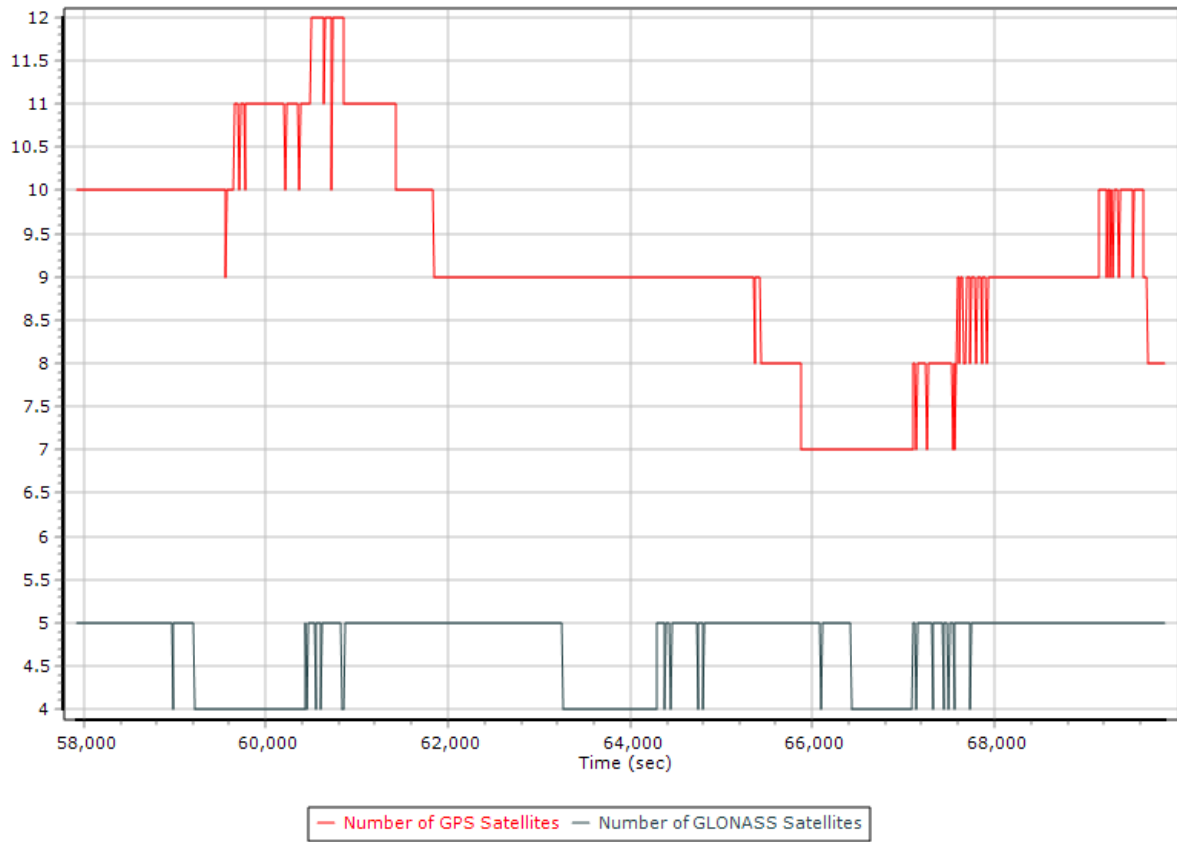
X:

Y:

Z:









Project Settings

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

Timing

Start: 57913.977
End: 69894.418

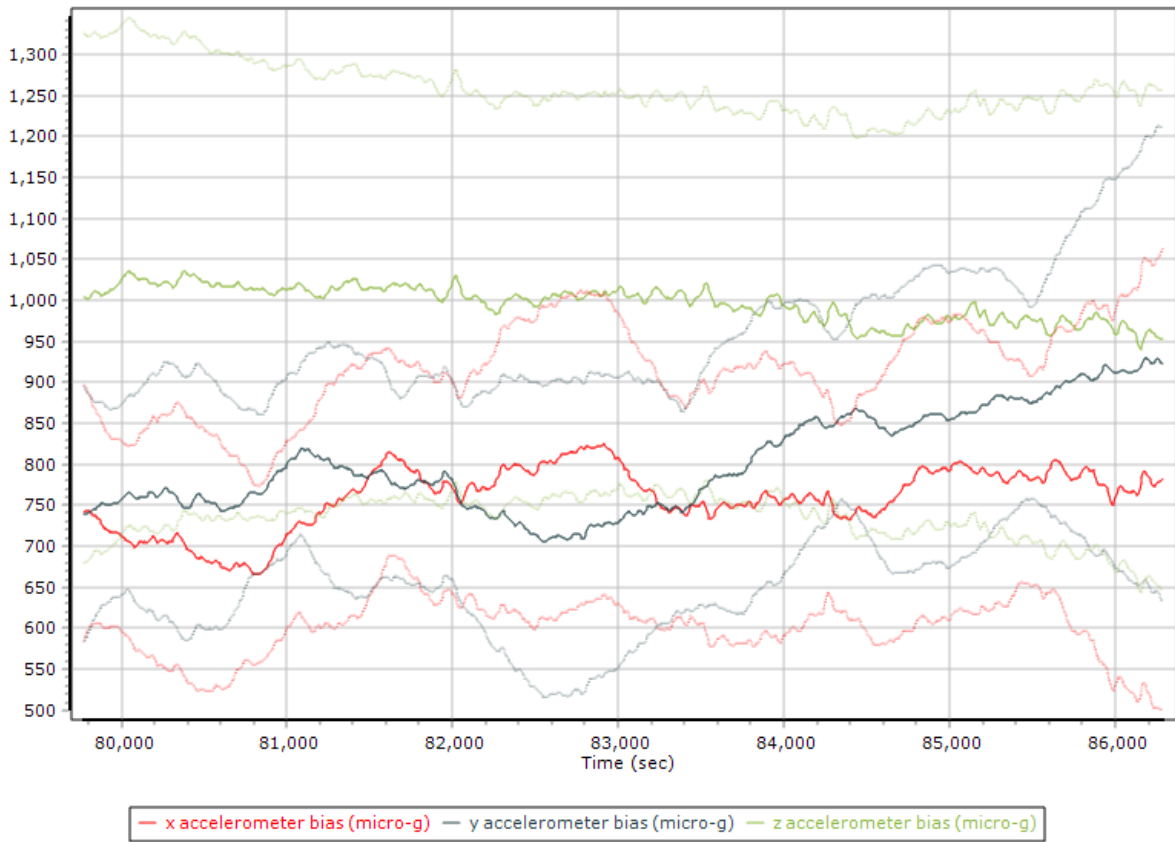
Entire time interval
 Seconds of start week

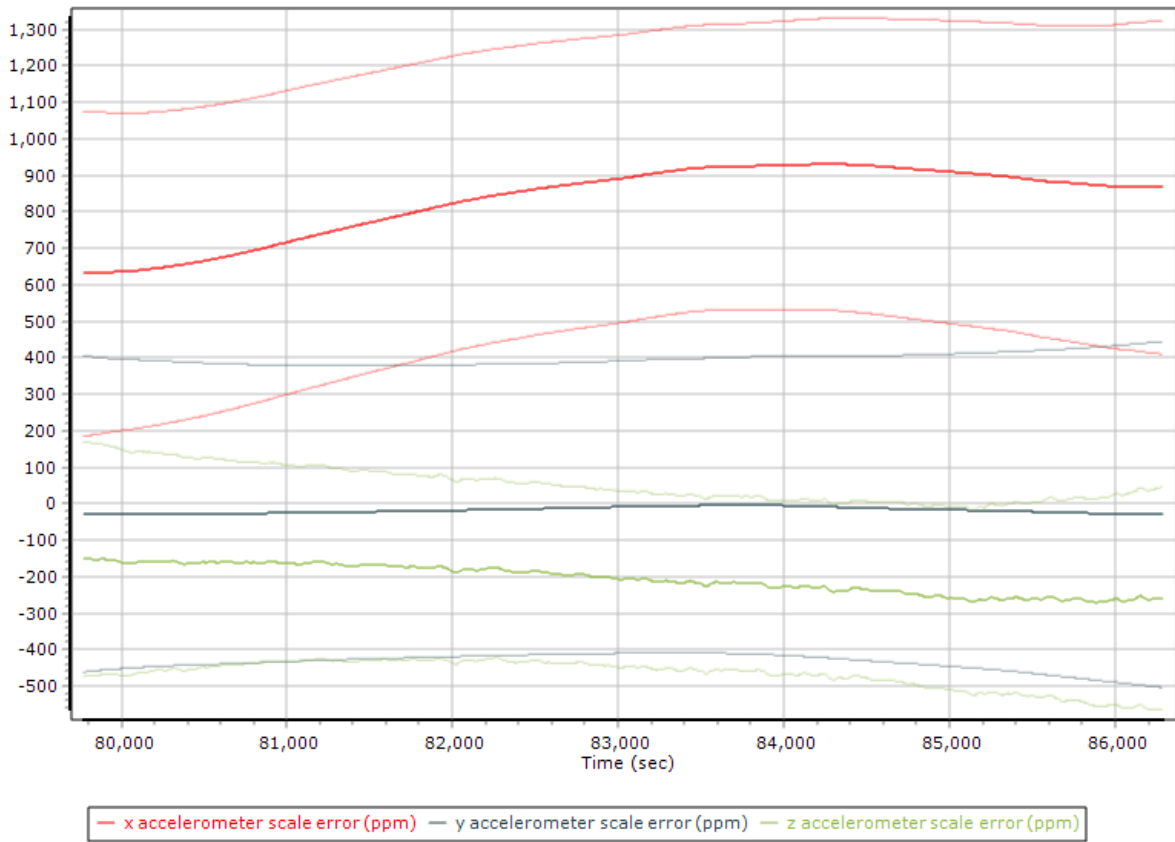
UTC Offset: 18.000

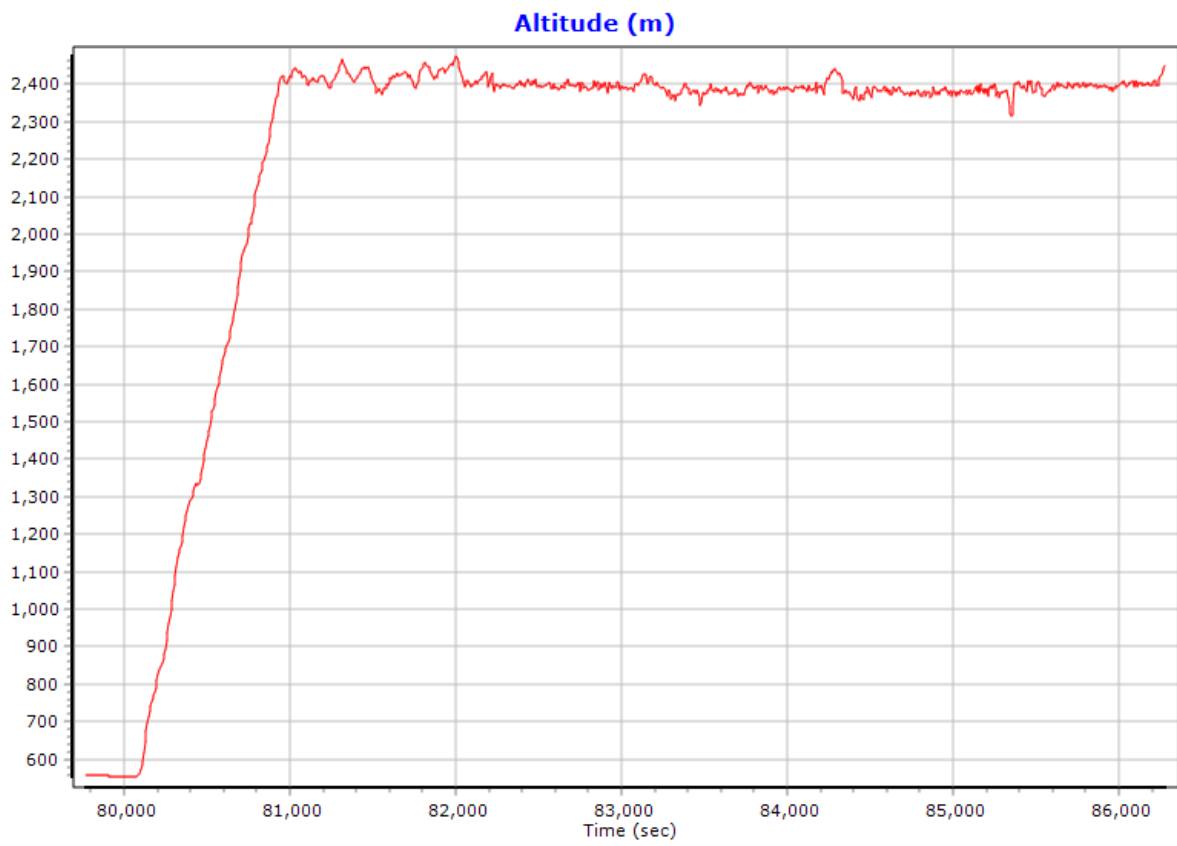
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

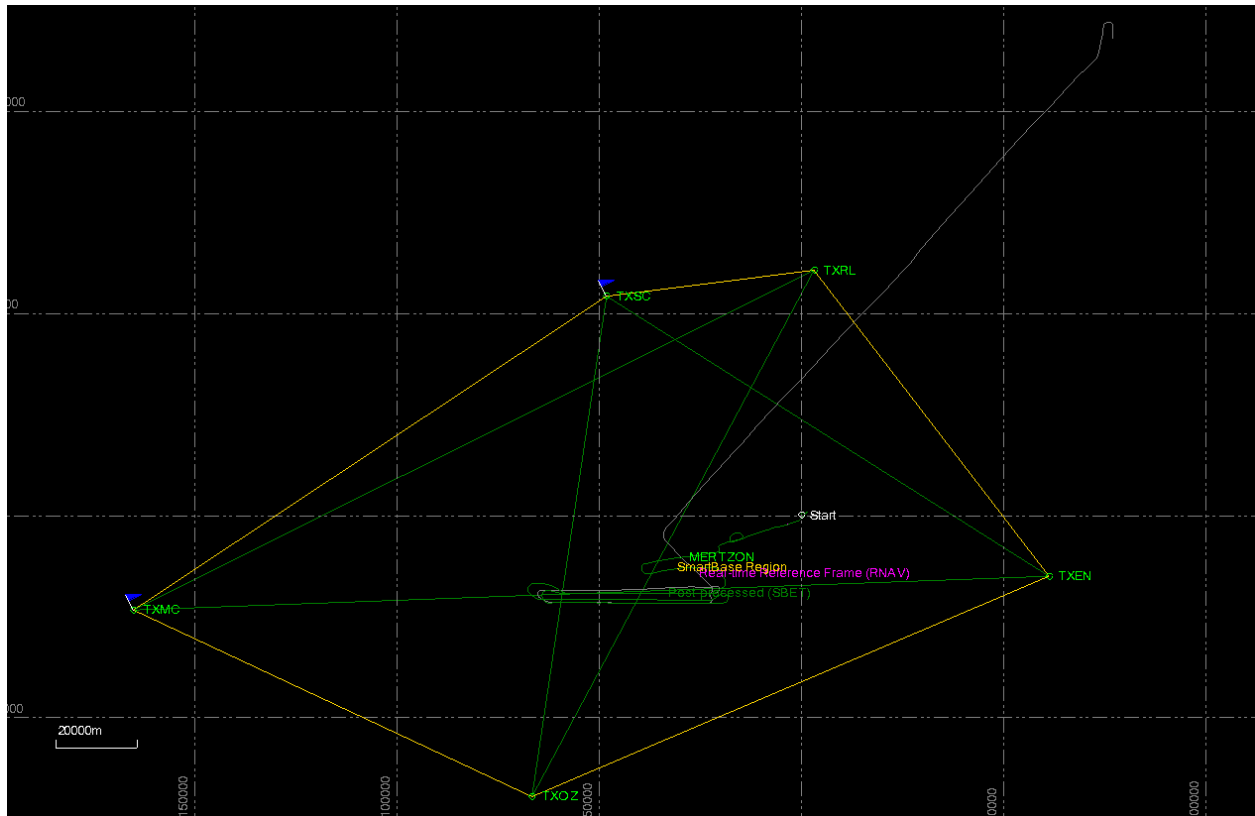
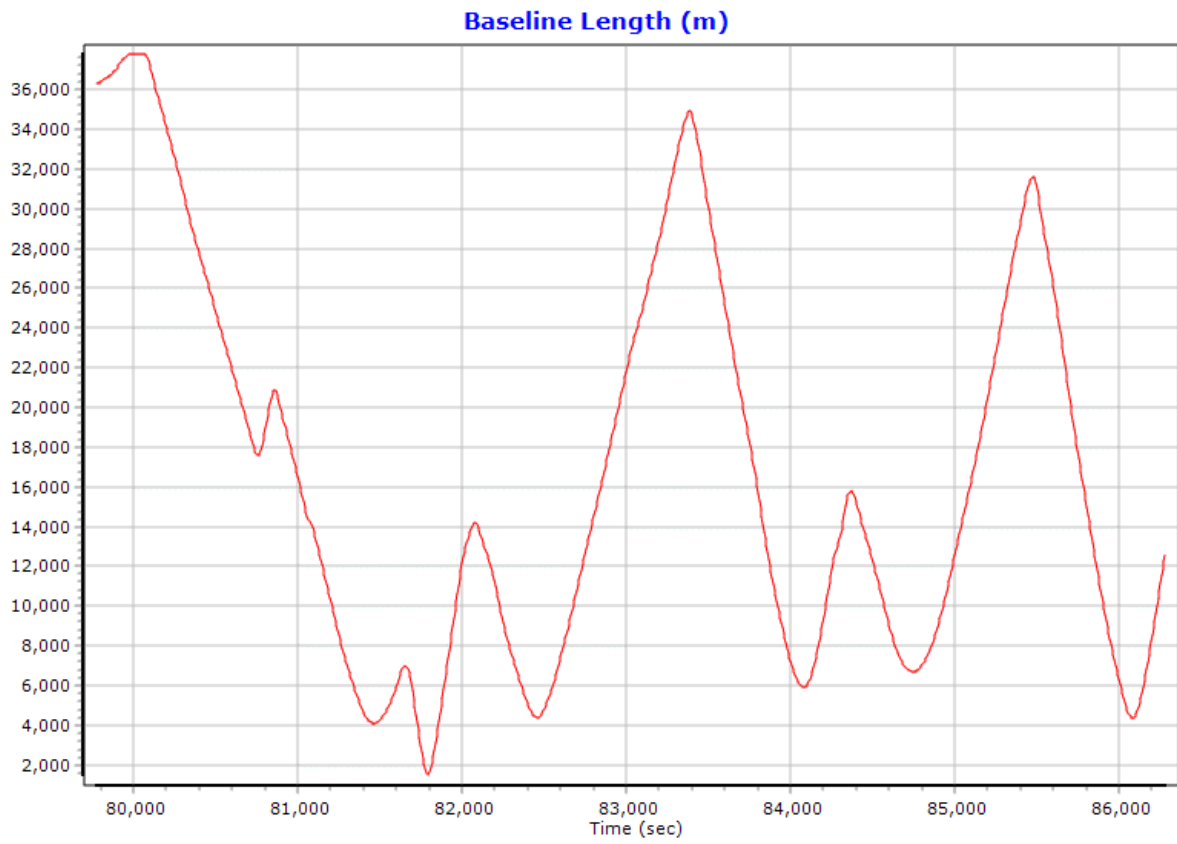
OK Cancel

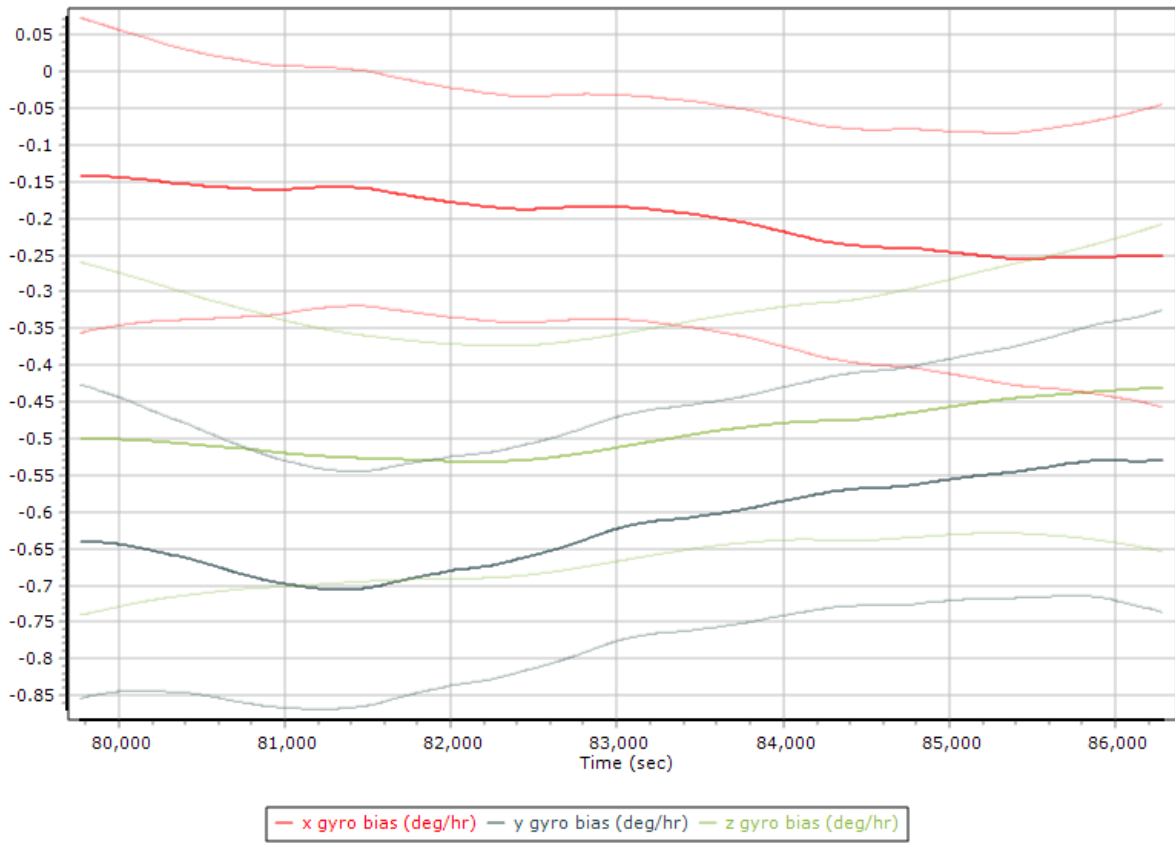
UNB18056B

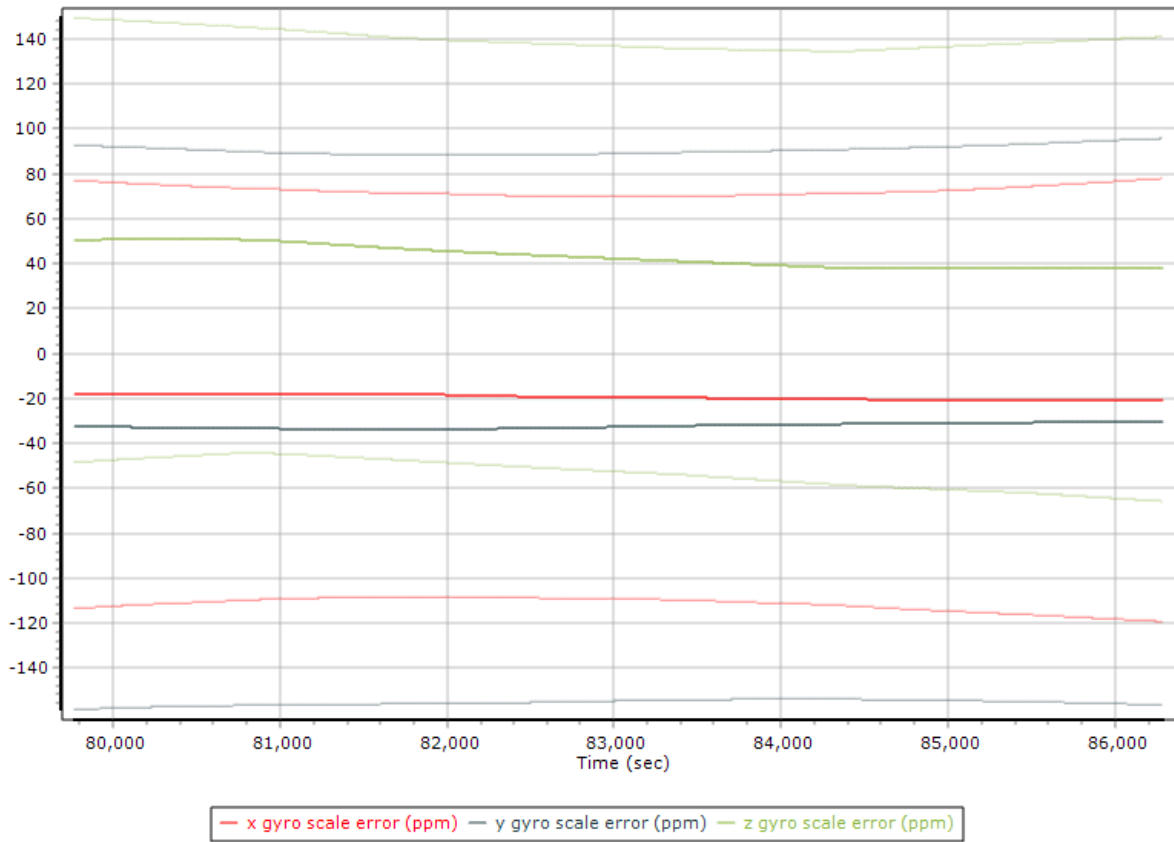












Project Settings [X]

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

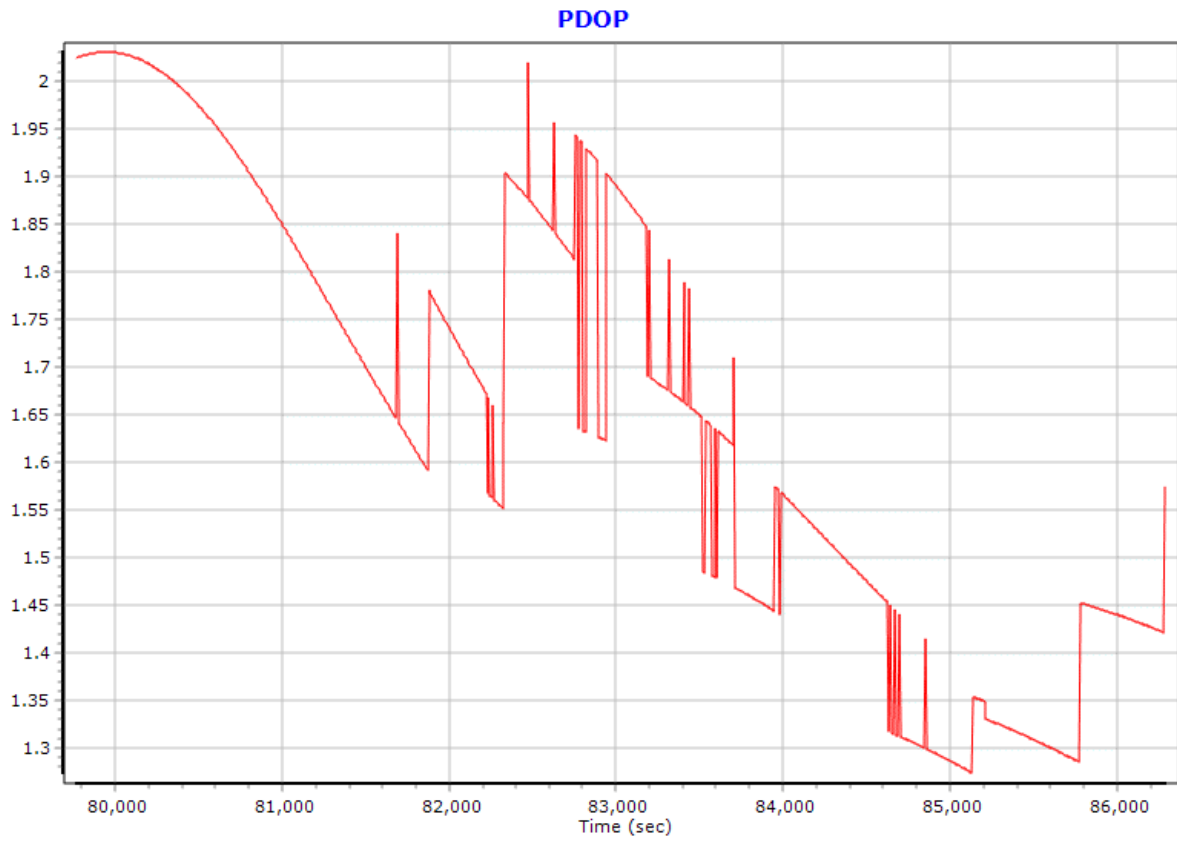
Aircraft to Reference Mounting Angles

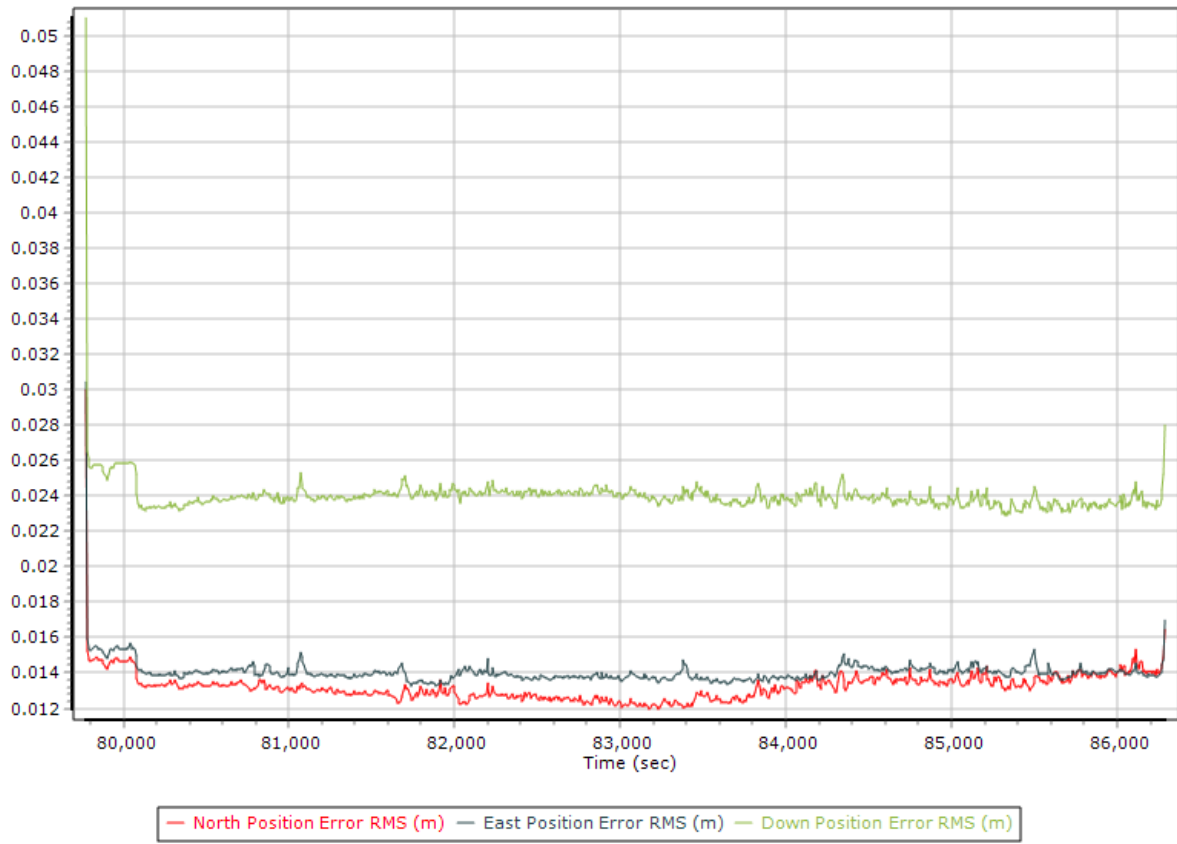
X:

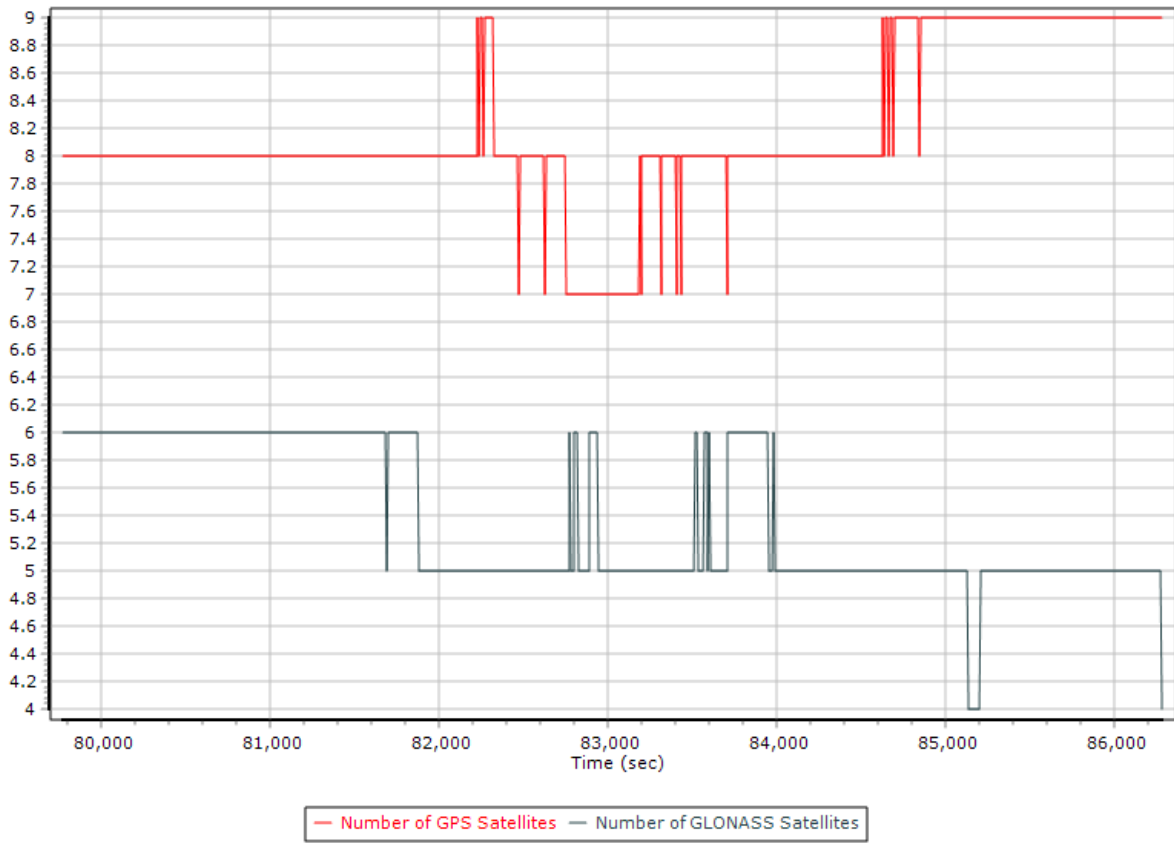
Y:

Z:

OK Cancel









Project Settings [X]

- General Information
- Units
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 - Timing**
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LIDAR
- SAR

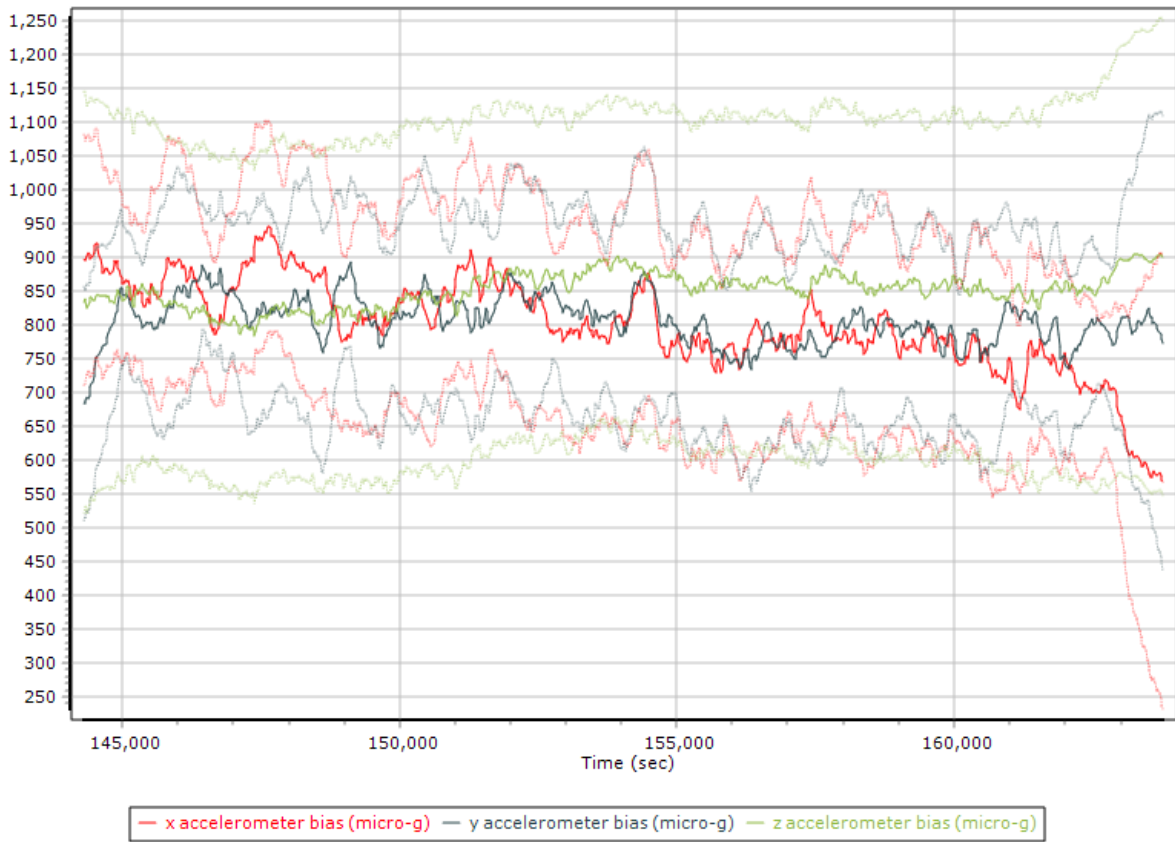
Timing

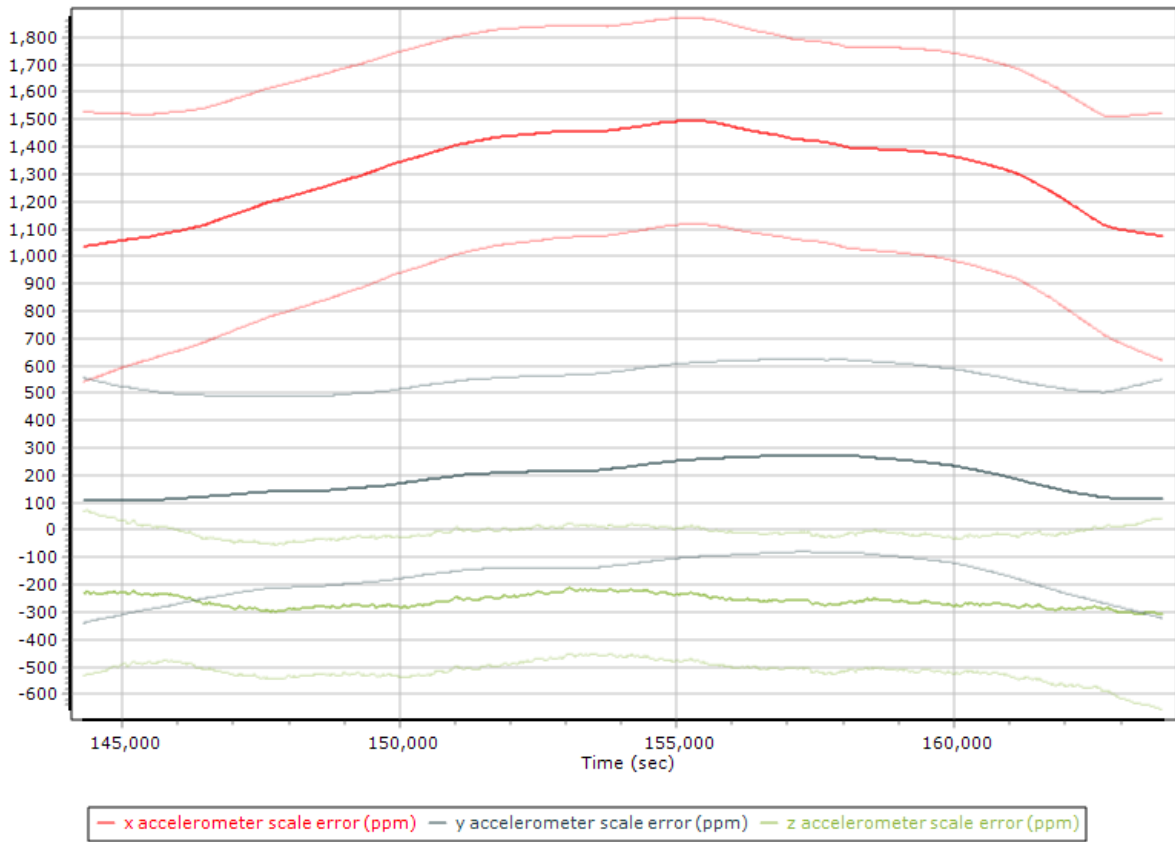
Start: 78971.000
 End: 86289.669
 Entire time interval
 Seconds of start week
 UTC Offset: 18.000

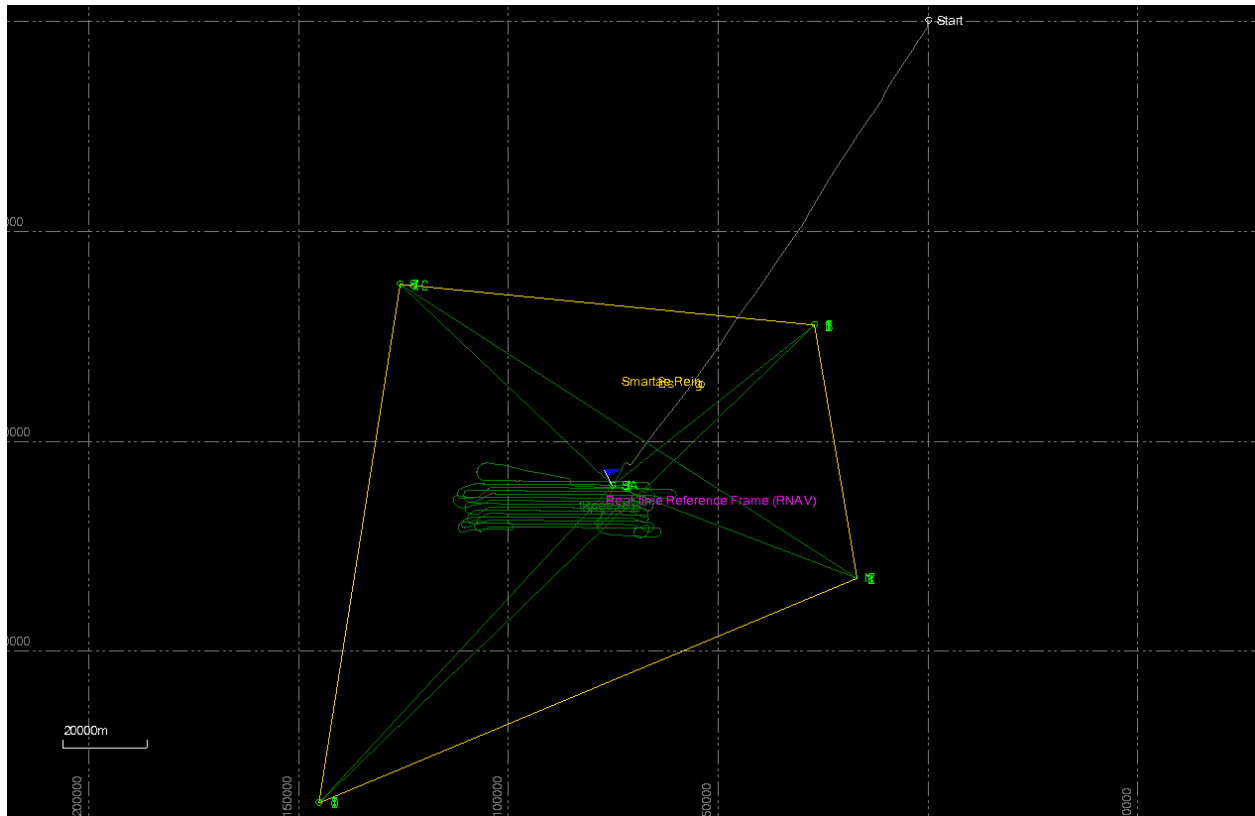
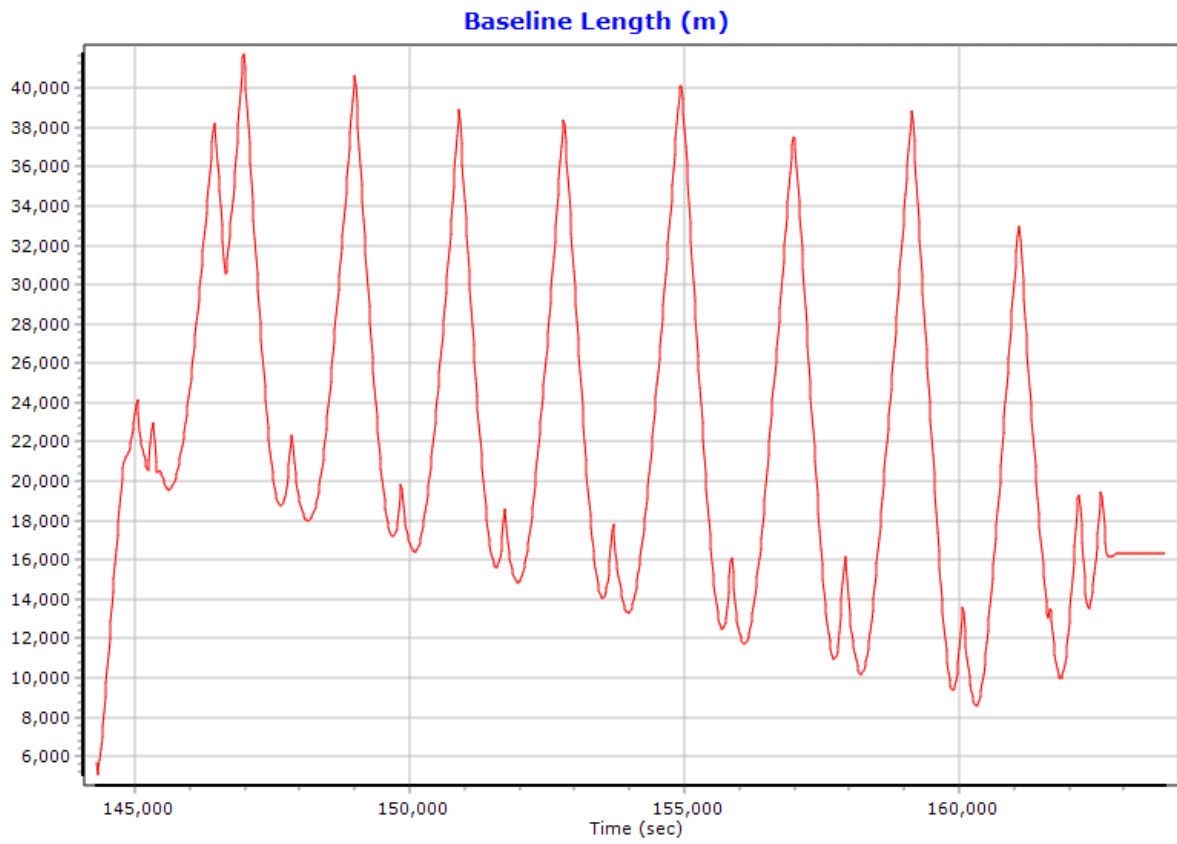
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

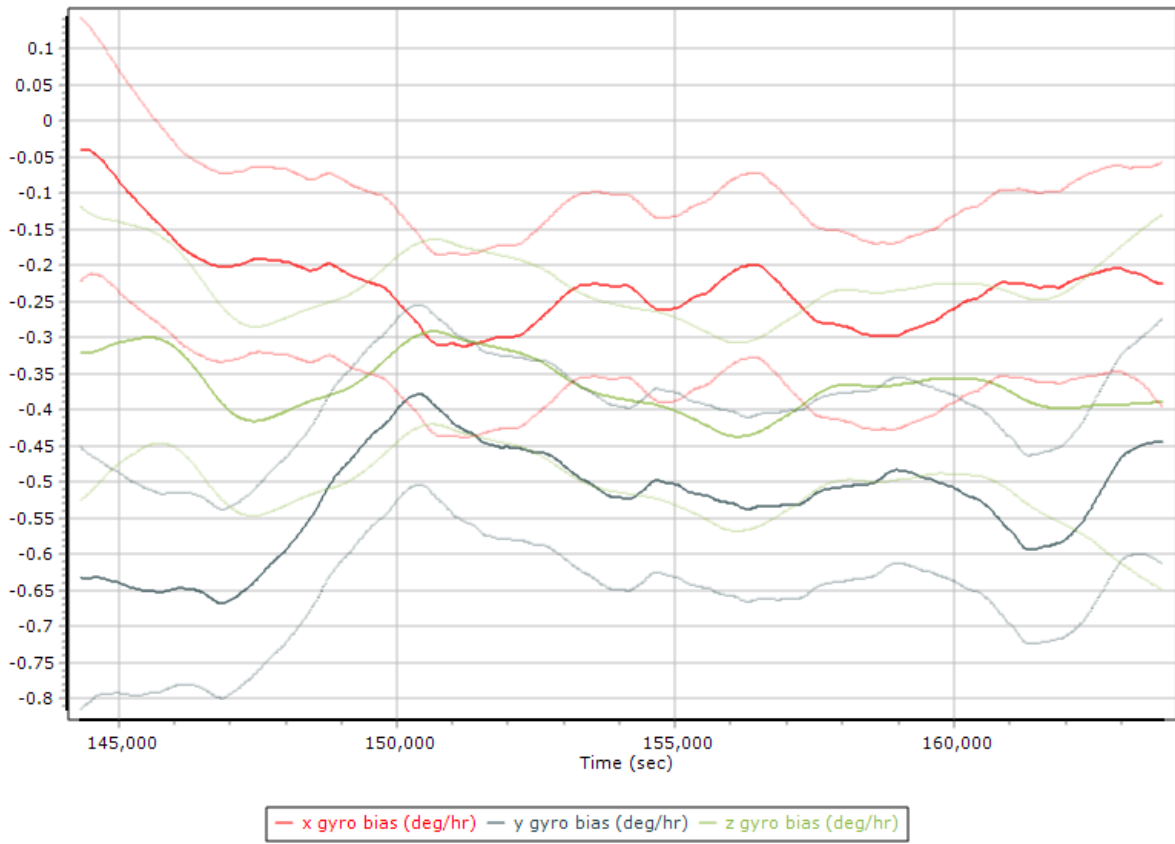
OK Cancel

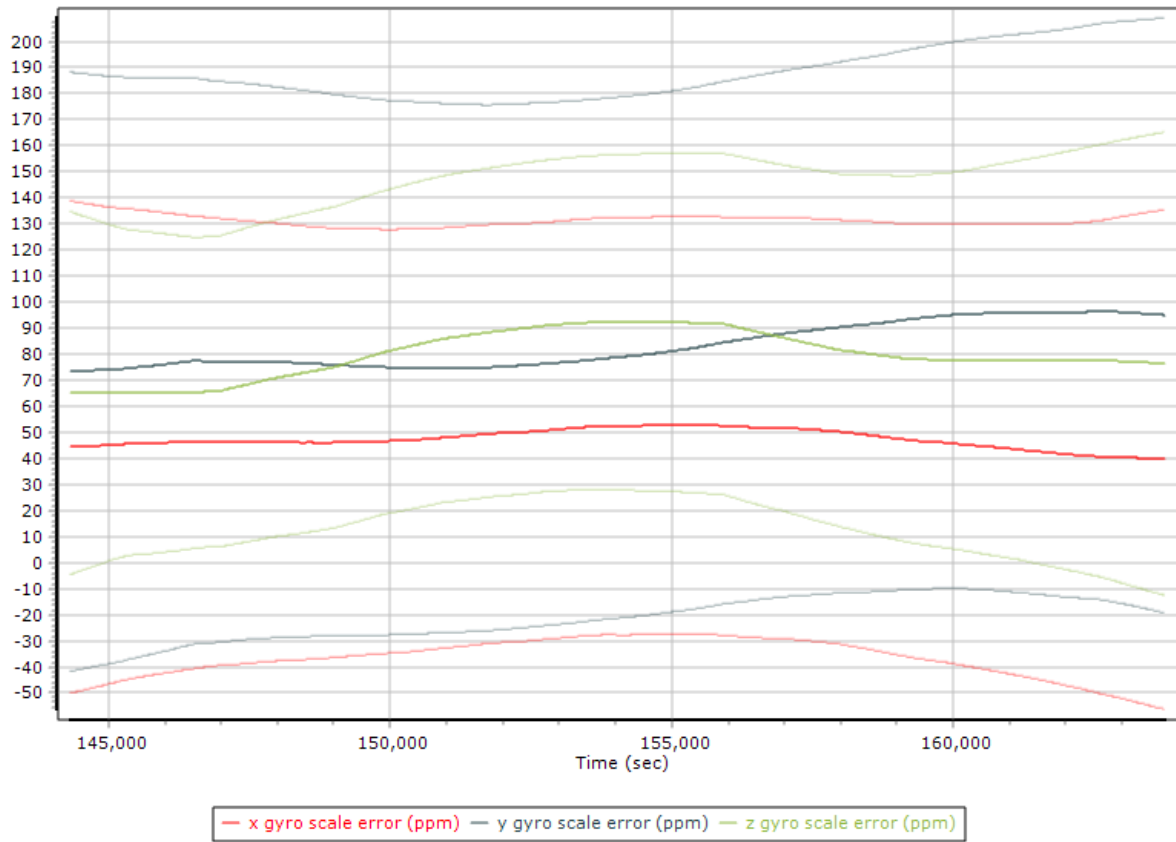
UNB18057A











Project Settings

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

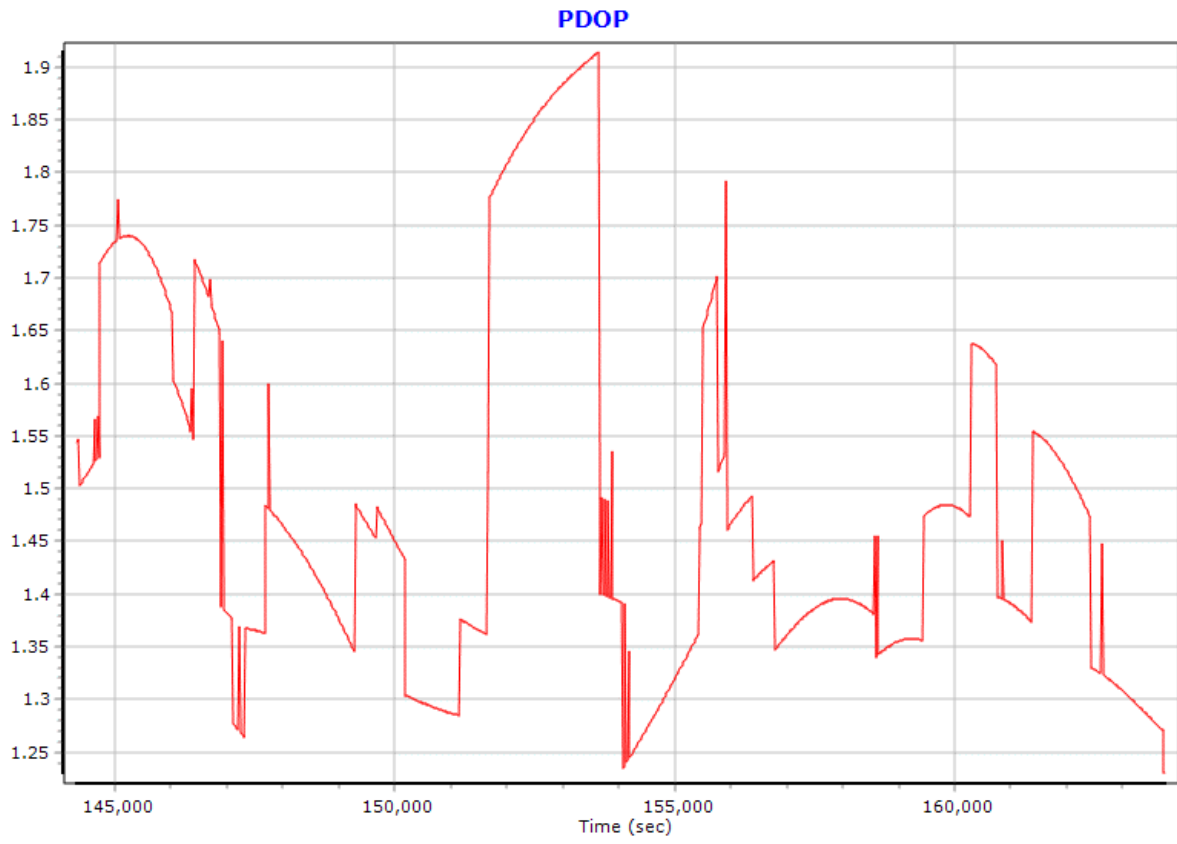
Aircraft to Reference Mounting Angles

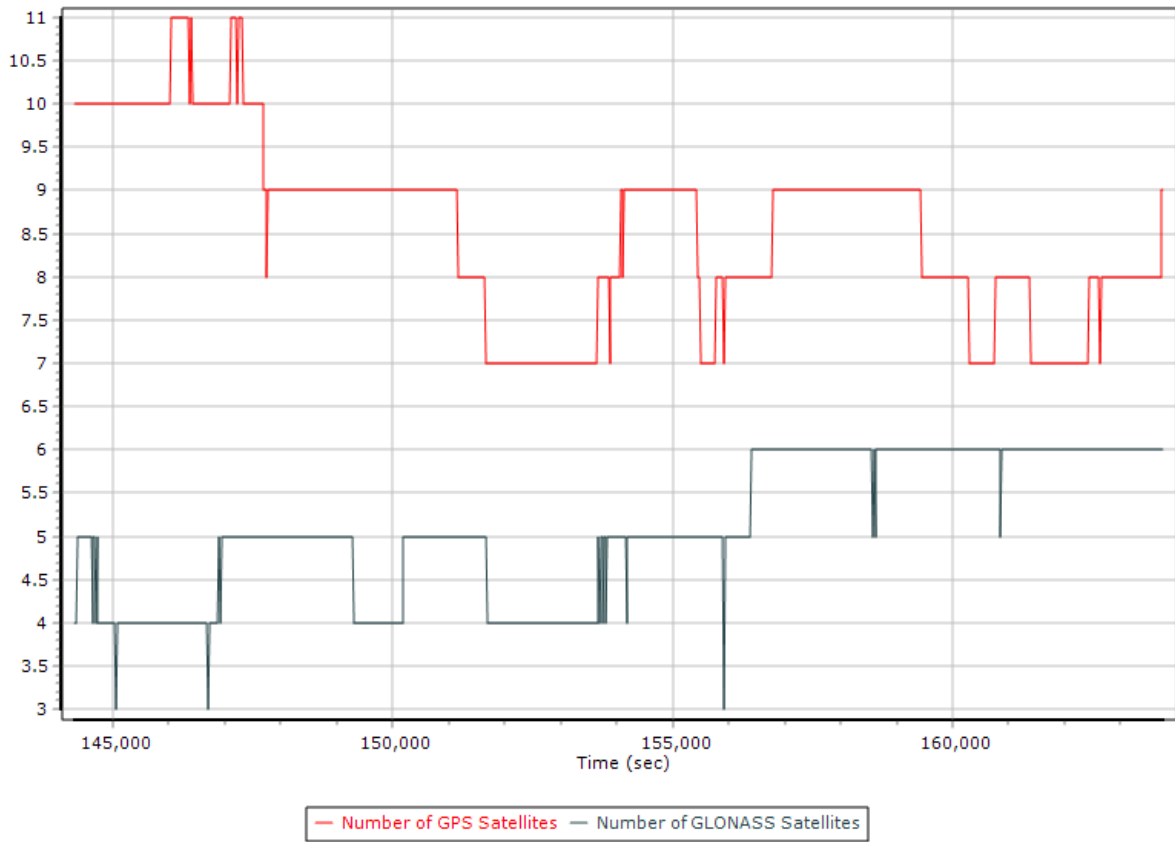
X:

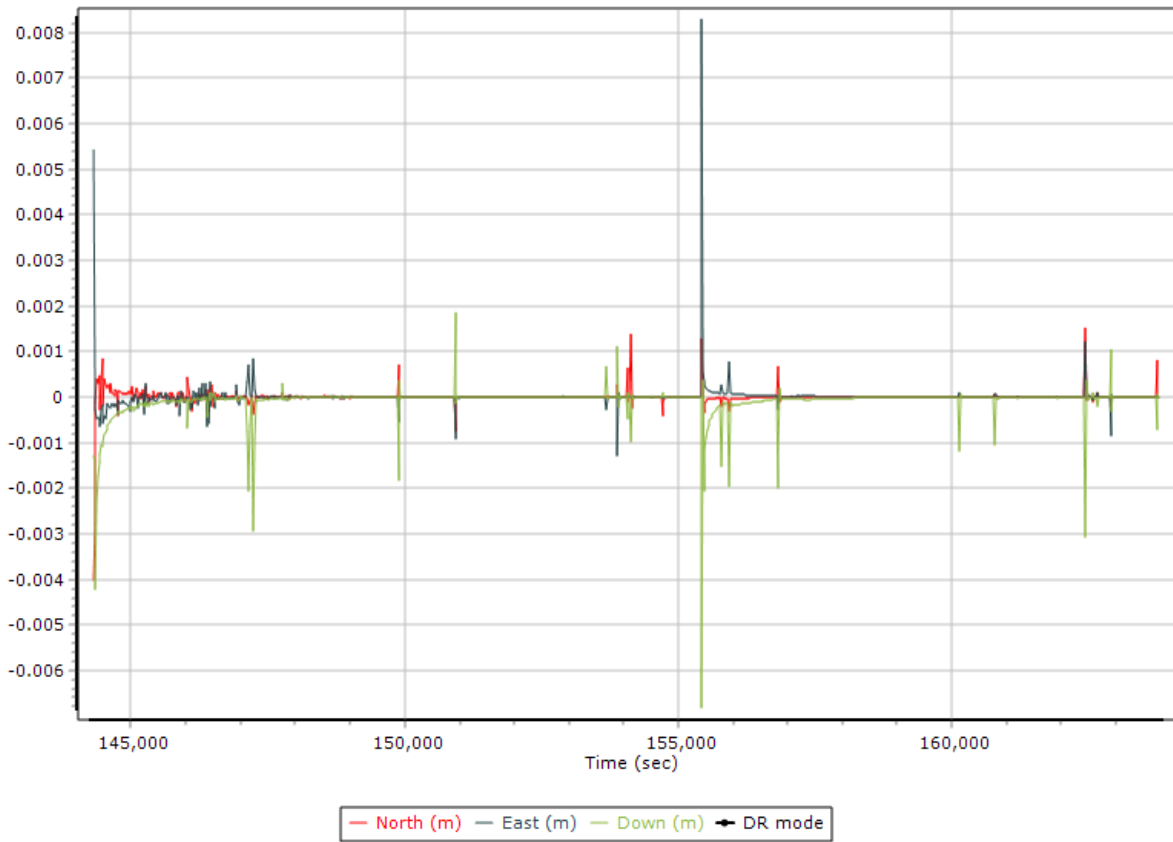
Y:

Z:

OK Cancel







Project Settings

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- LIDAR
- SAR

Timing

Start: 144312.803

End: 163792.000

Entire time interval

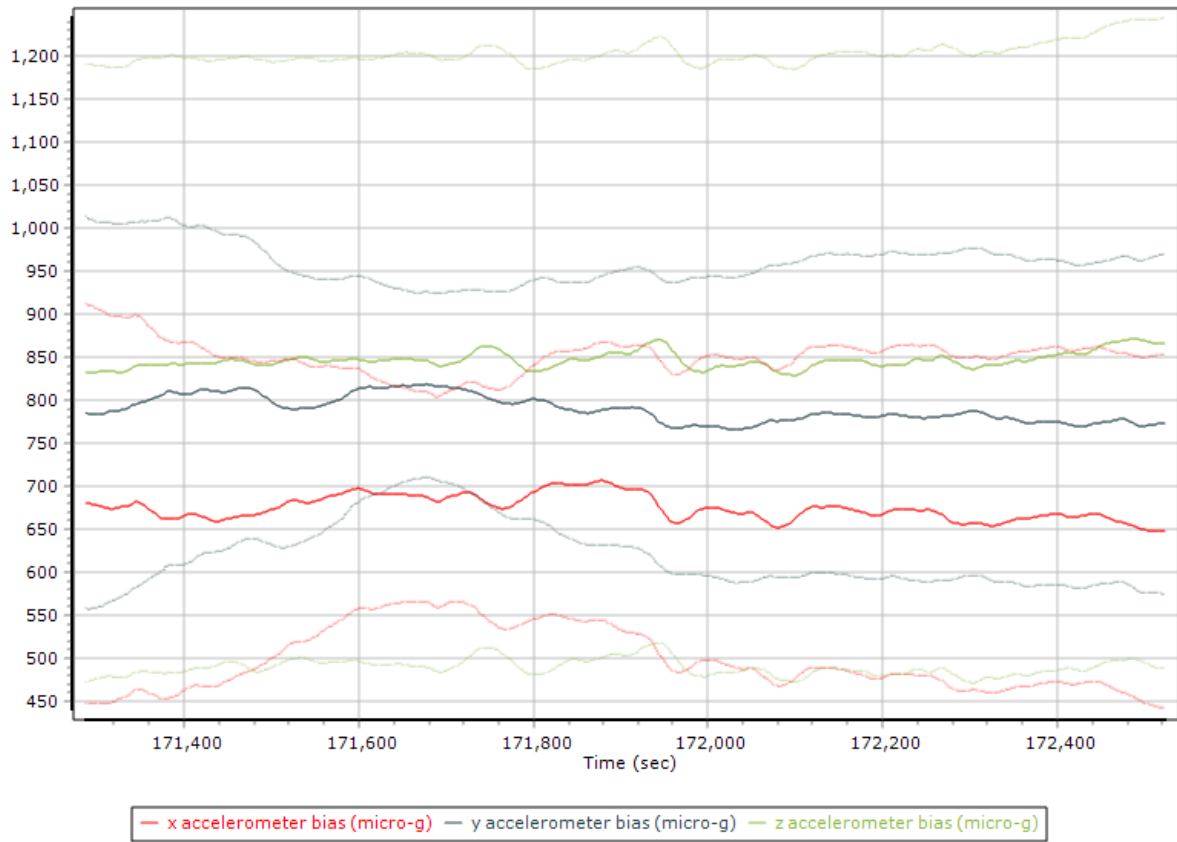
Seconds of start week

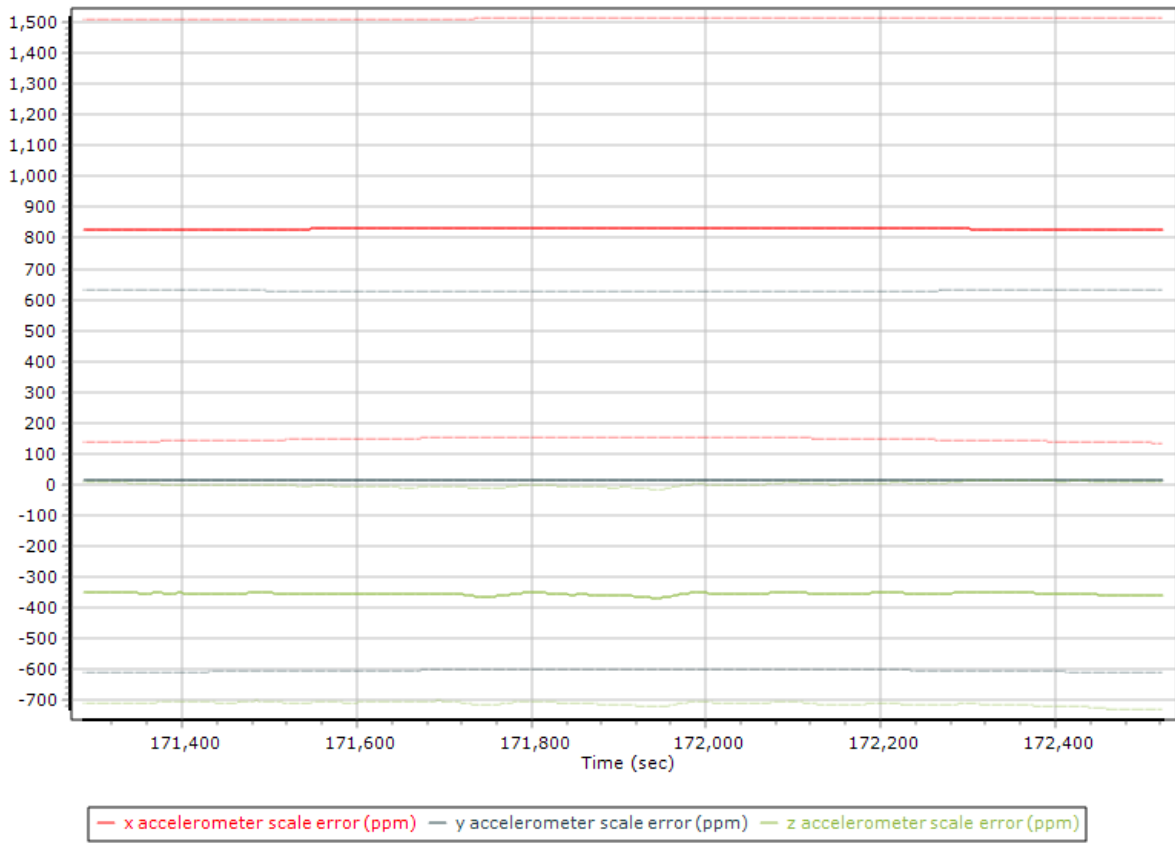
UTC Offset: 18.000

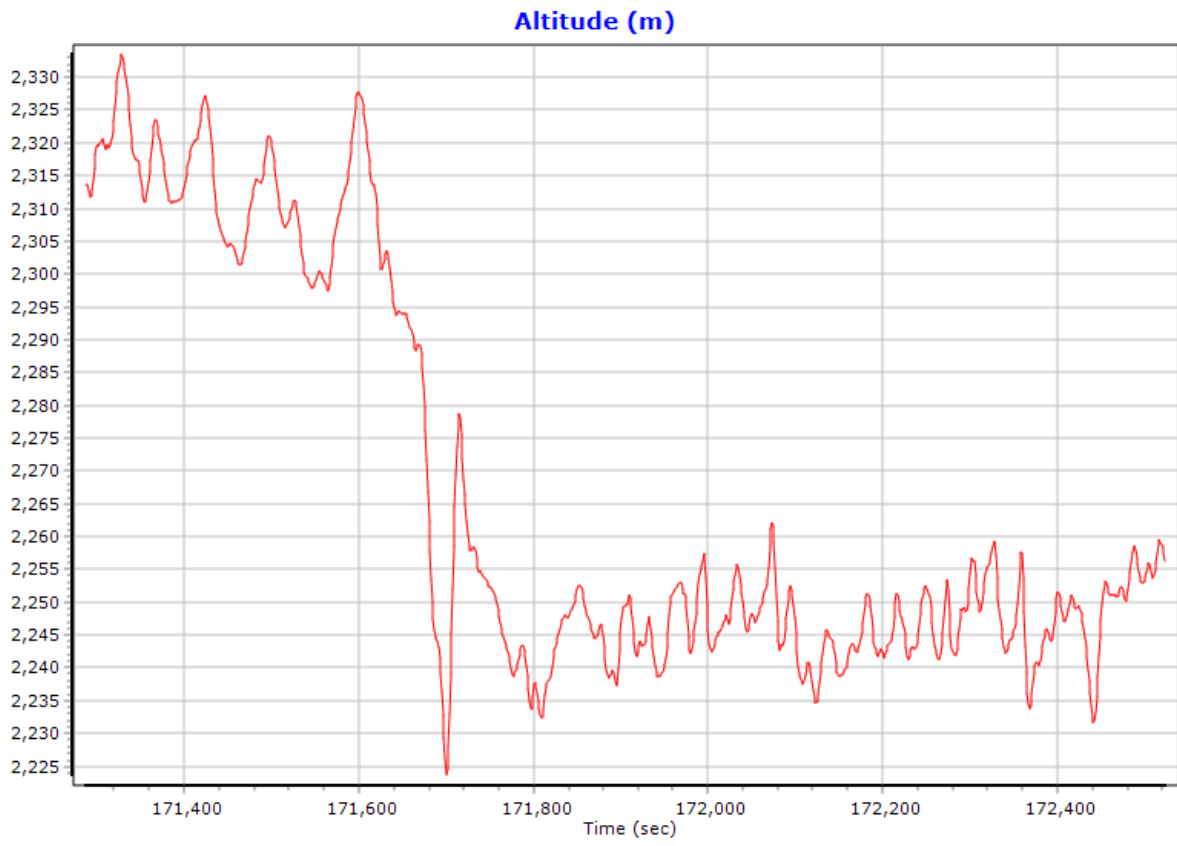
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel

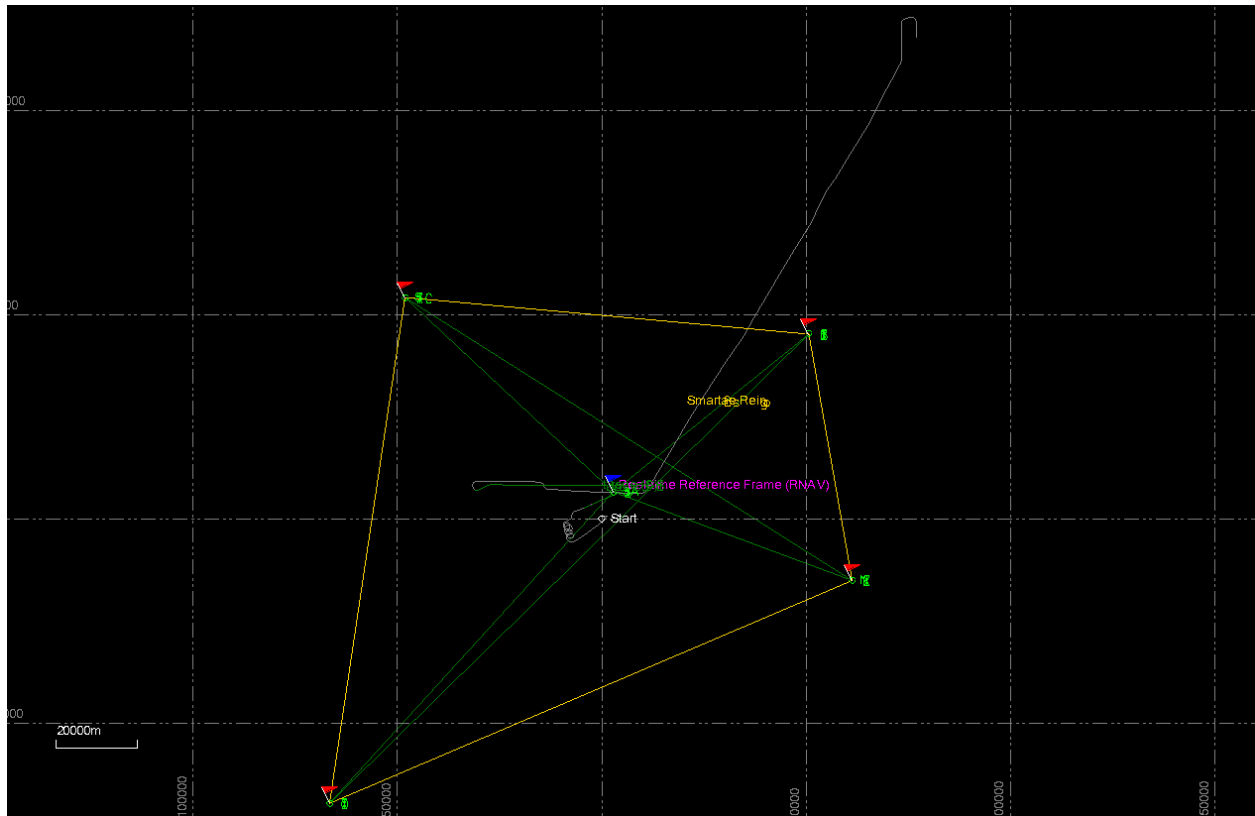
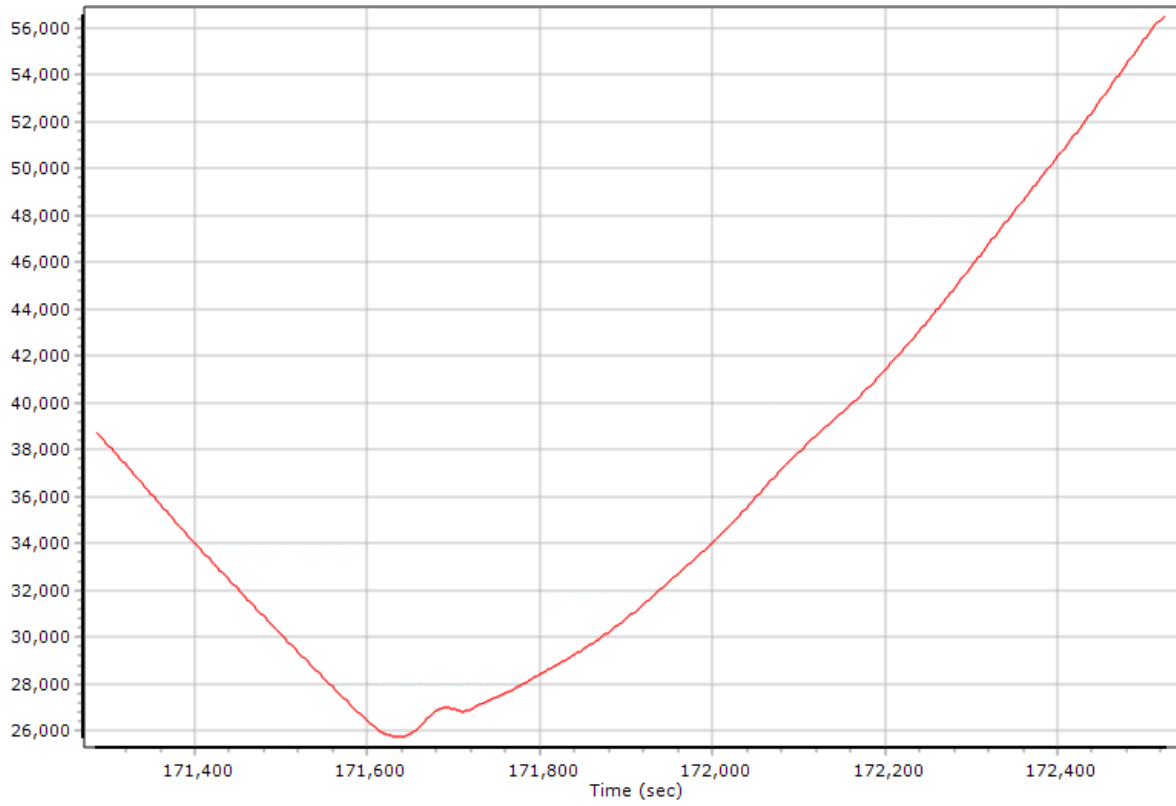
UNB18057B

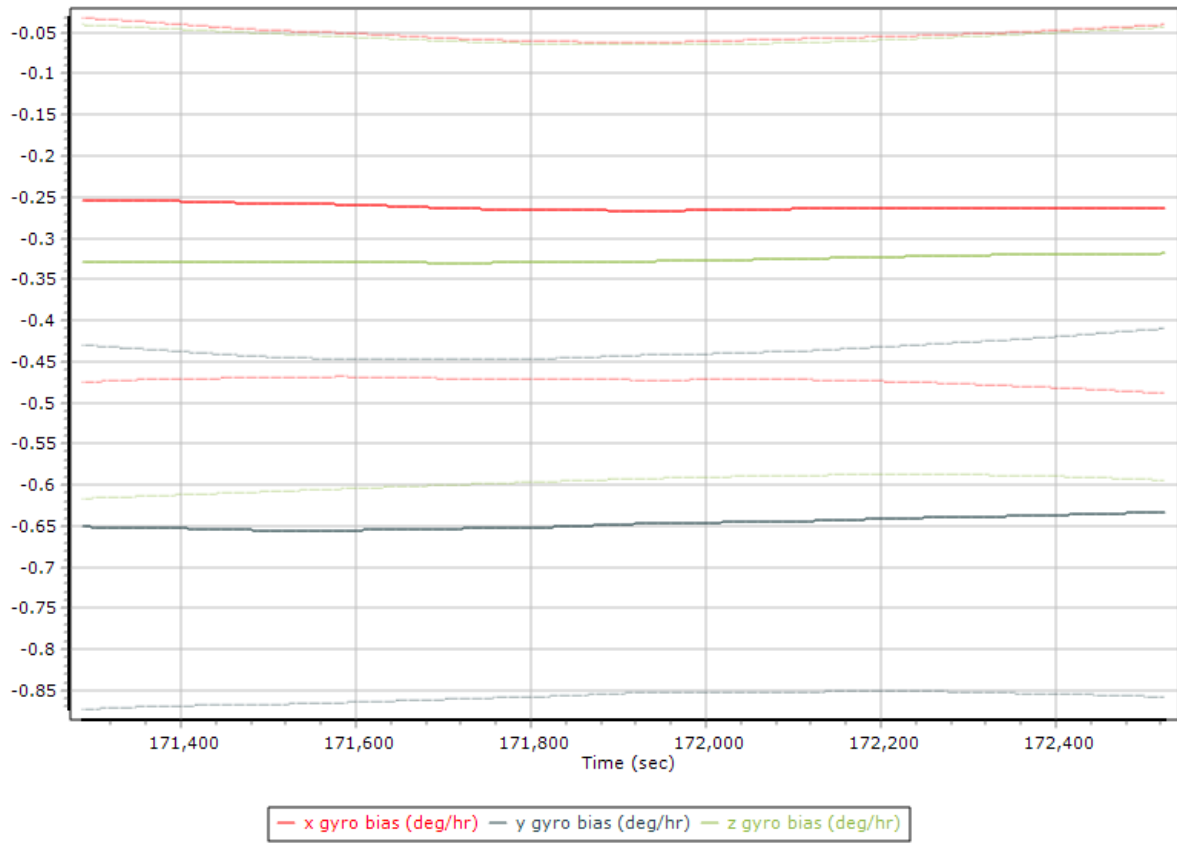


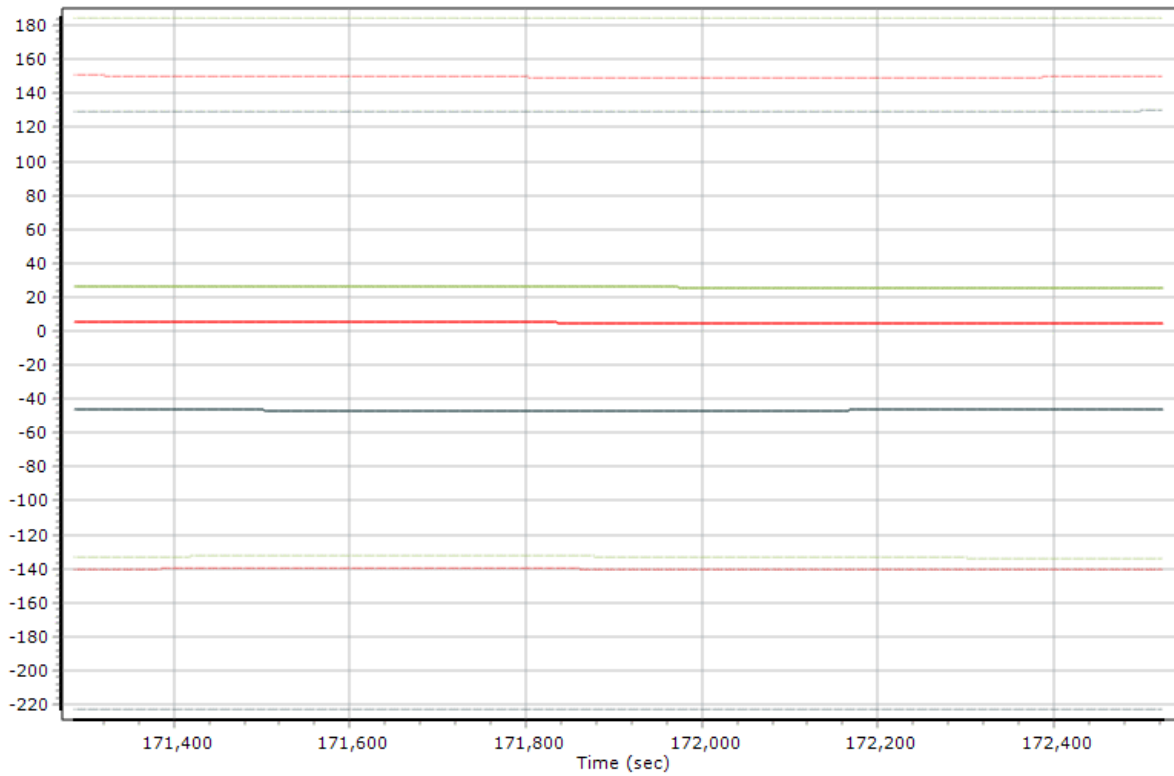




Baseline Length (m)







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

Project Settings ✕

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- SAR

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

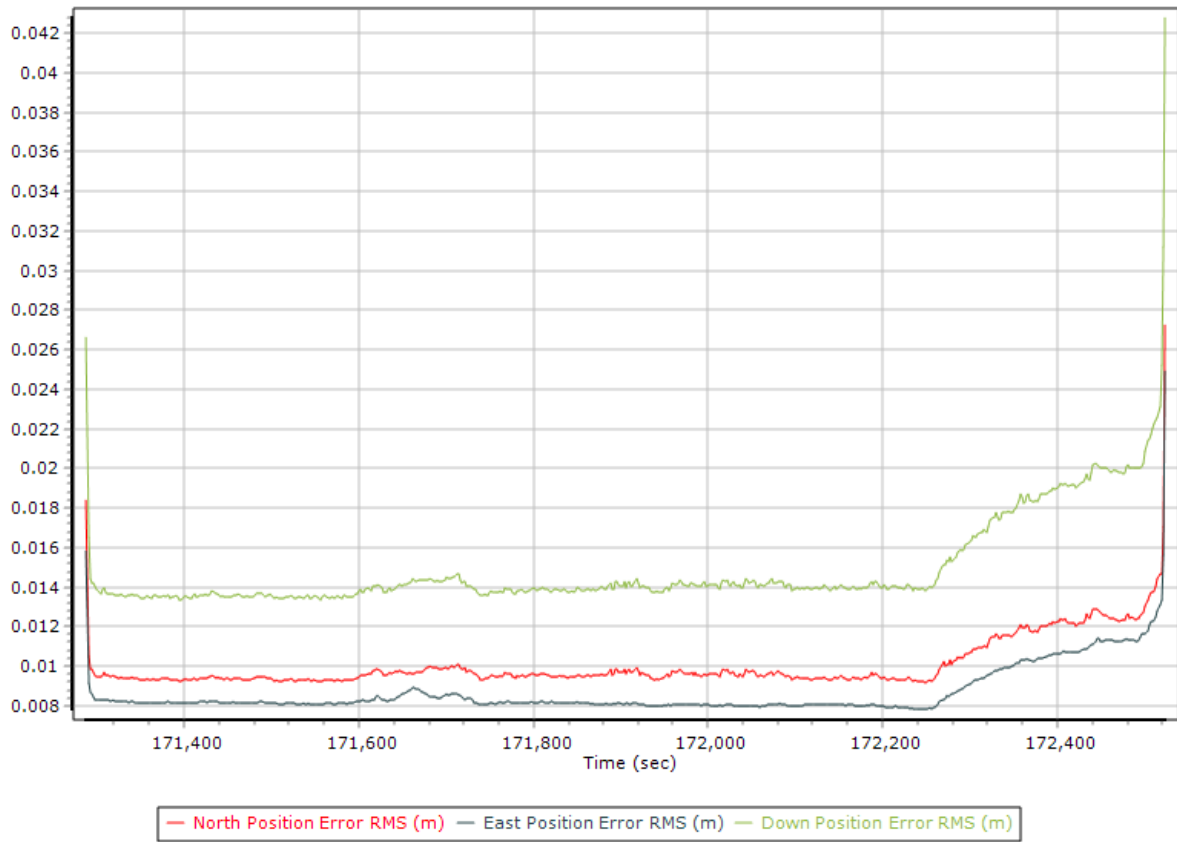
Aircraft to Reference Mounting Angles

X:

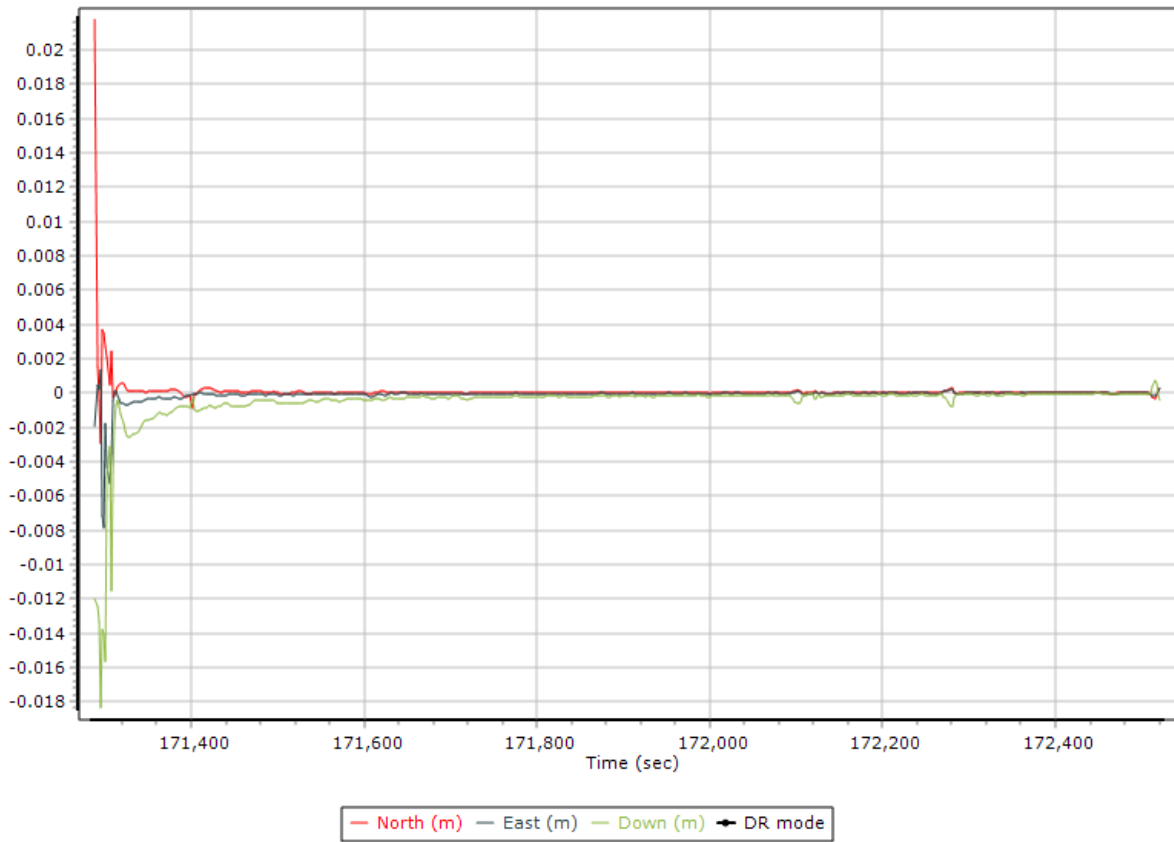
Y:

Z:









Project Settings [X]

- General Information
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 - Timing**
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
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Timing

Start: 171284.652
 End: 172524.845

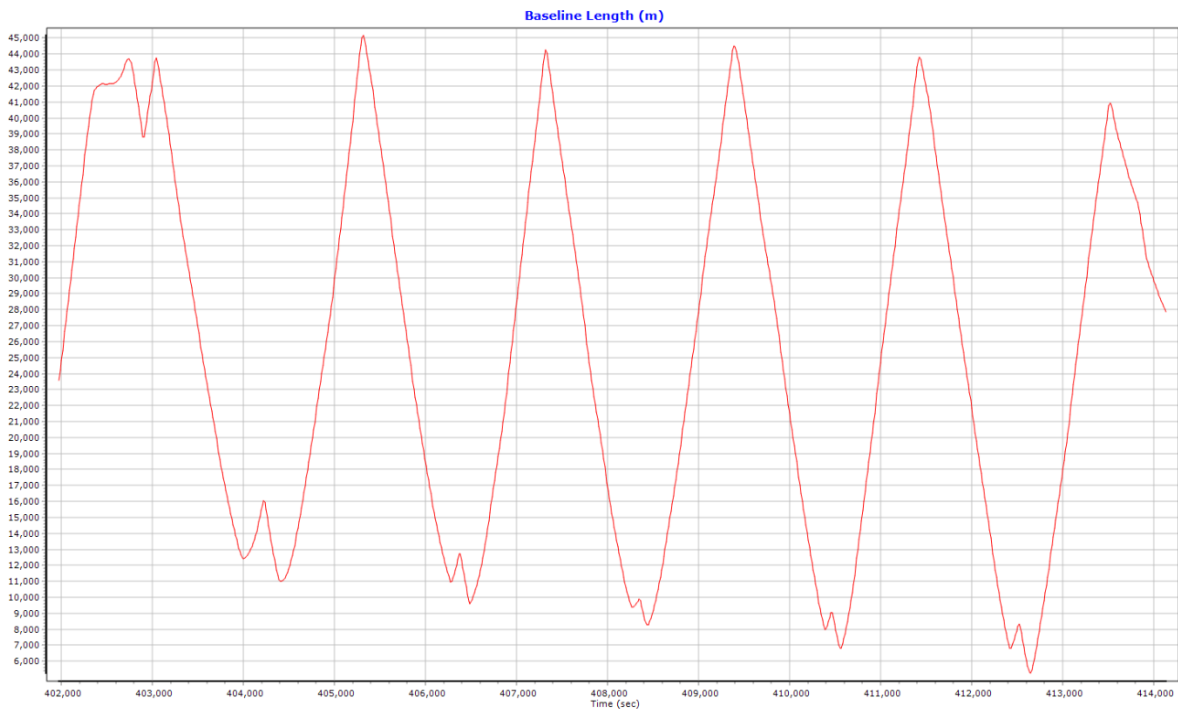
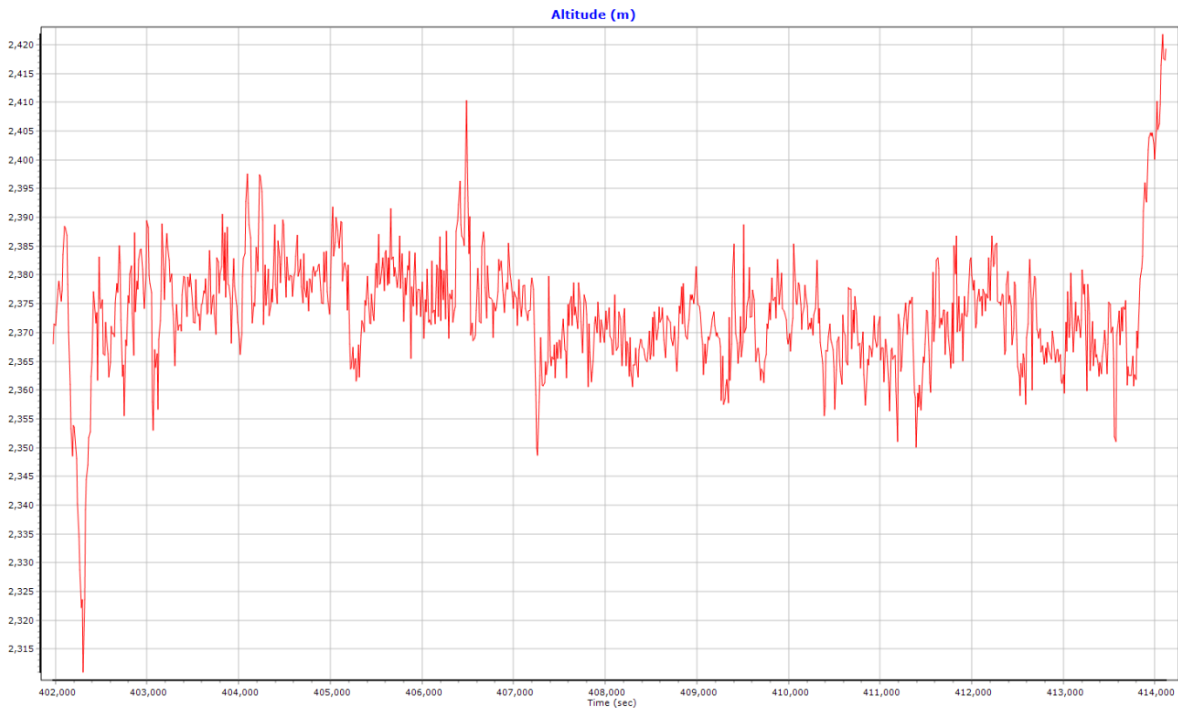
Entire time interval
 Seconds of start week

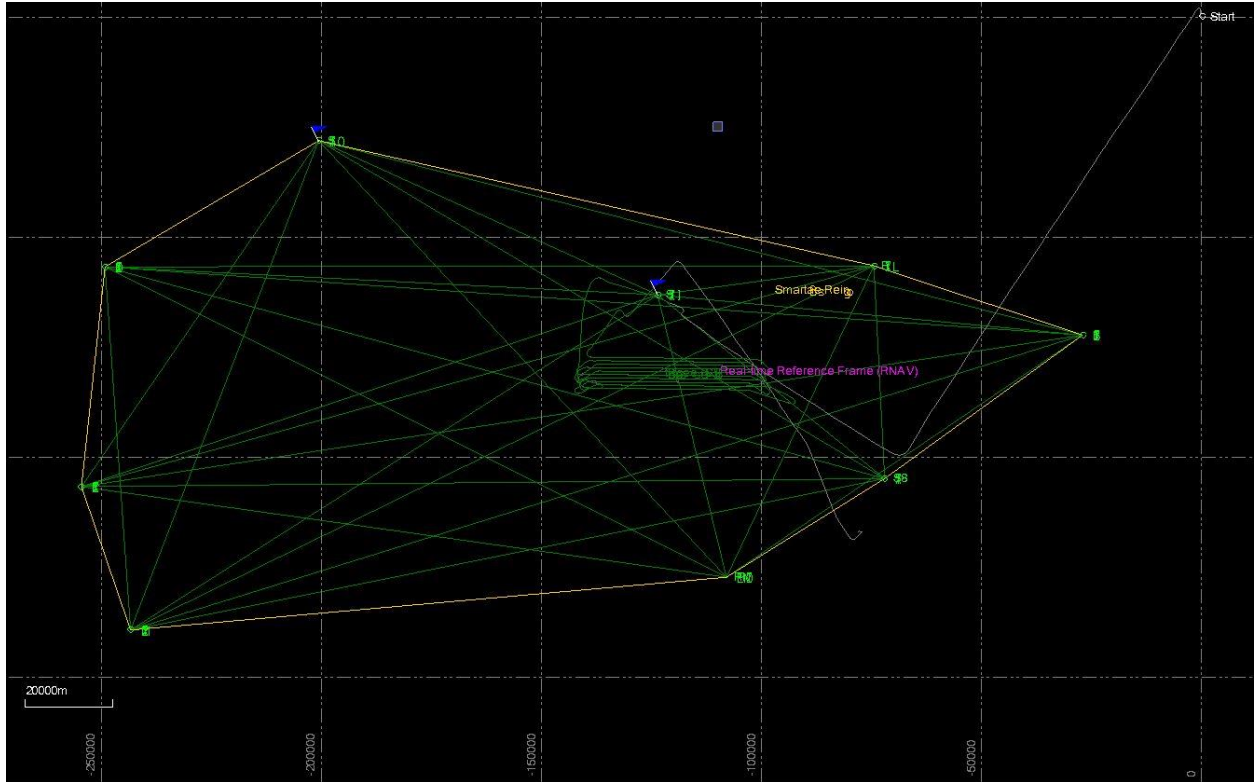
UTC Offset: 18.000

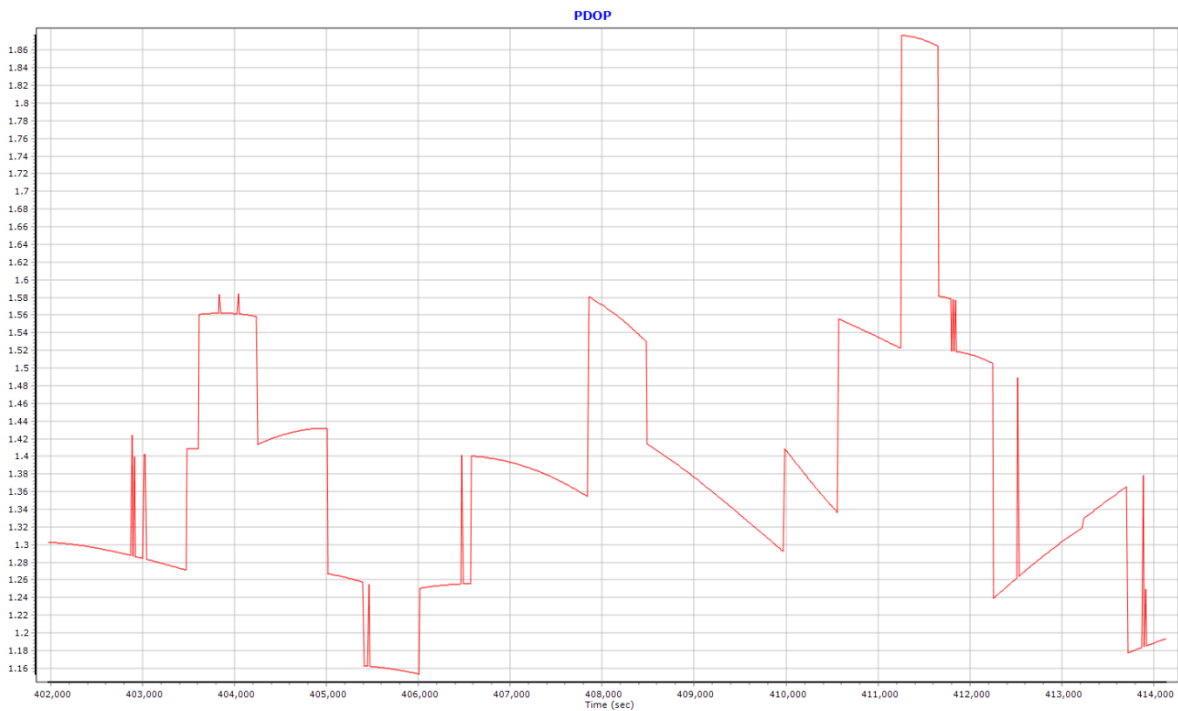
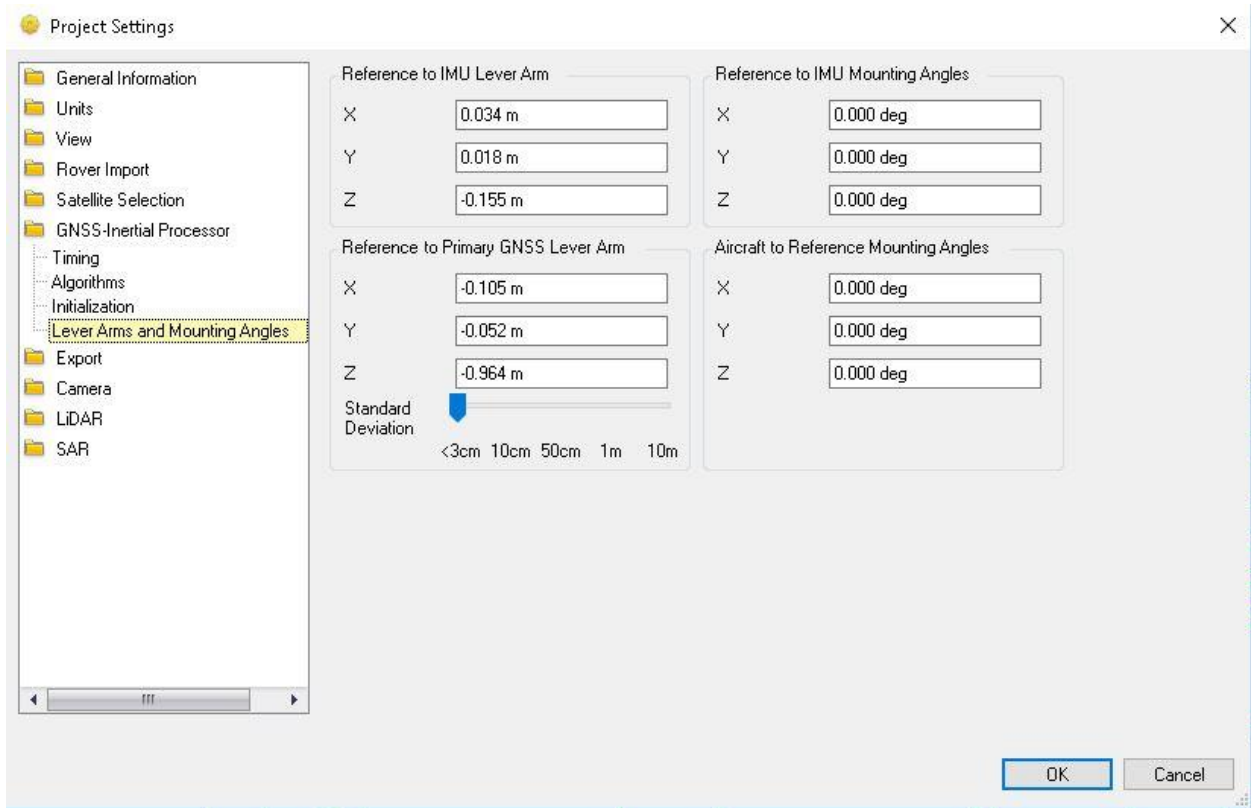
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

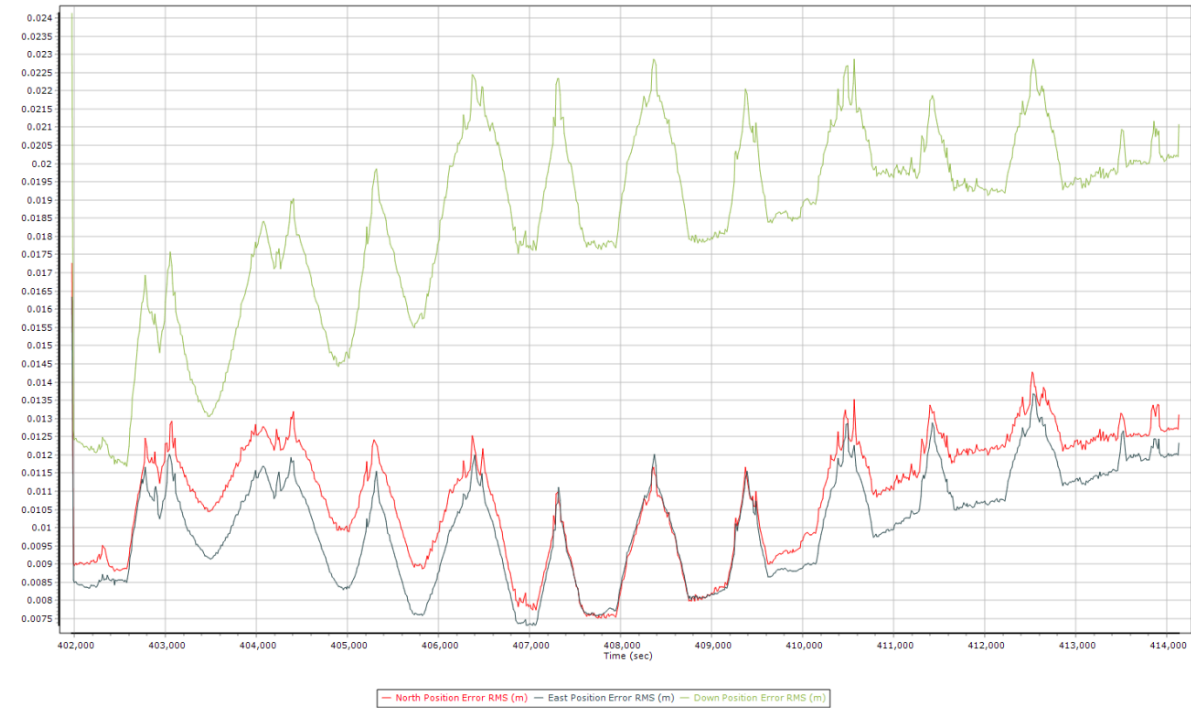
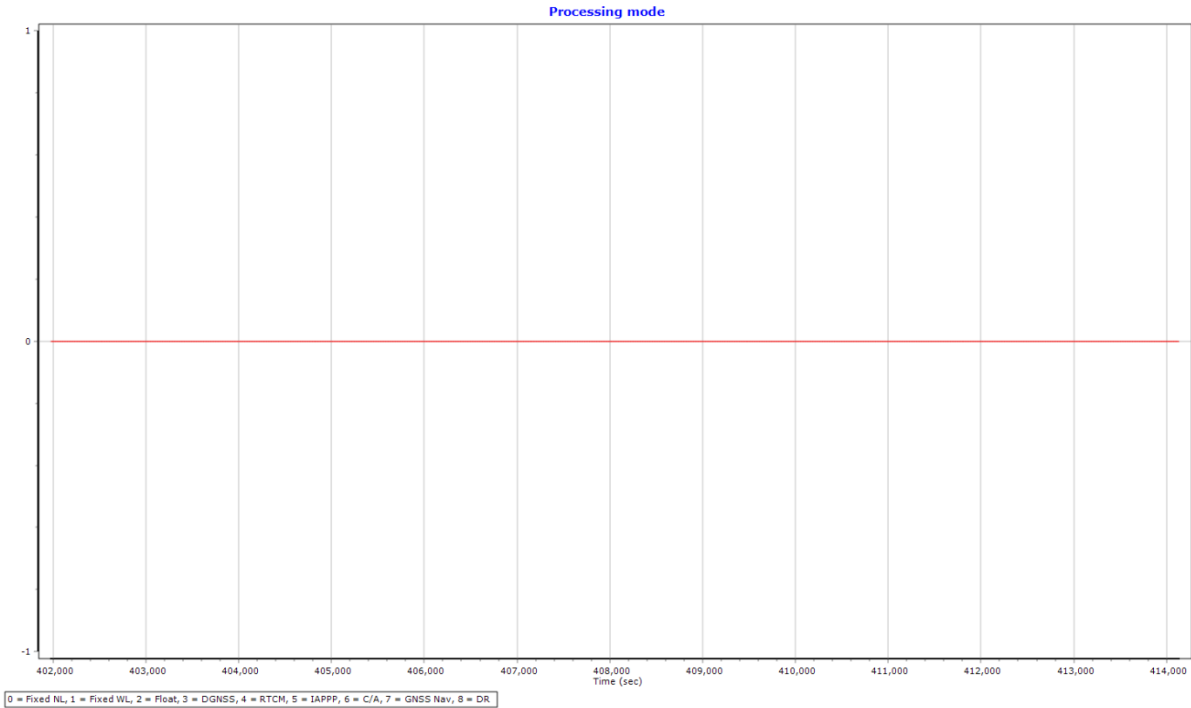
OK Cancel

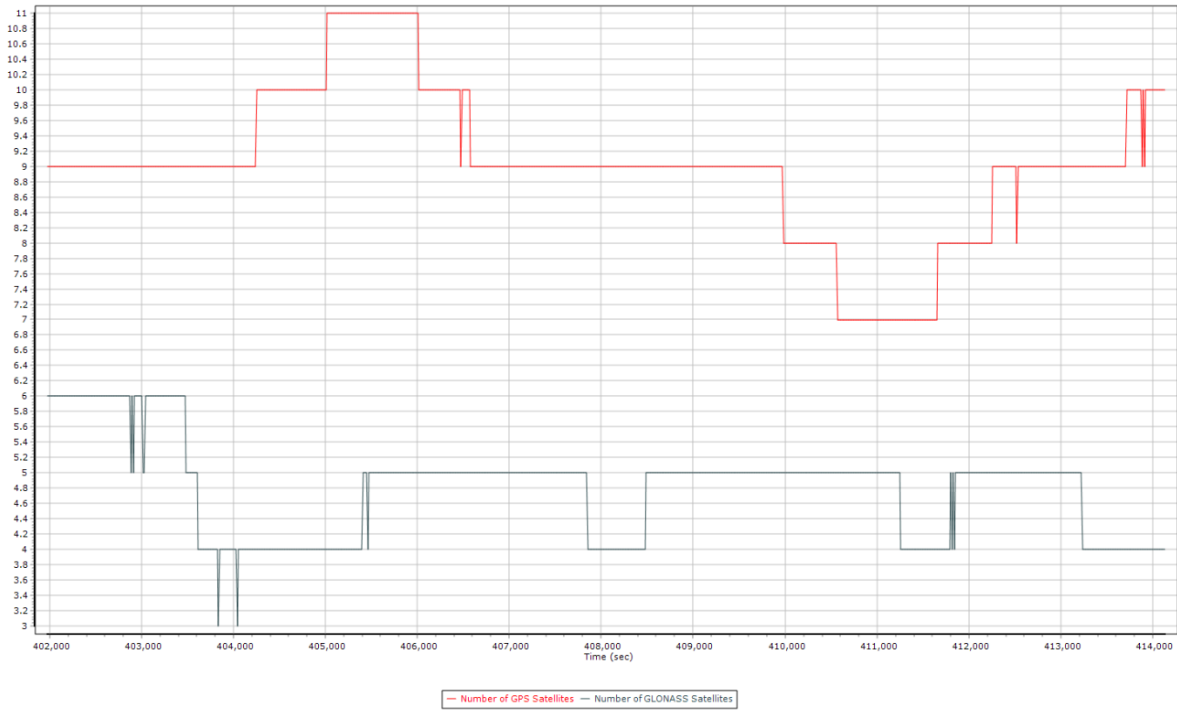
UNB18o6oA











Project Settings

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 - Timing**
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LIDAR
- SAR

Timing

Start:

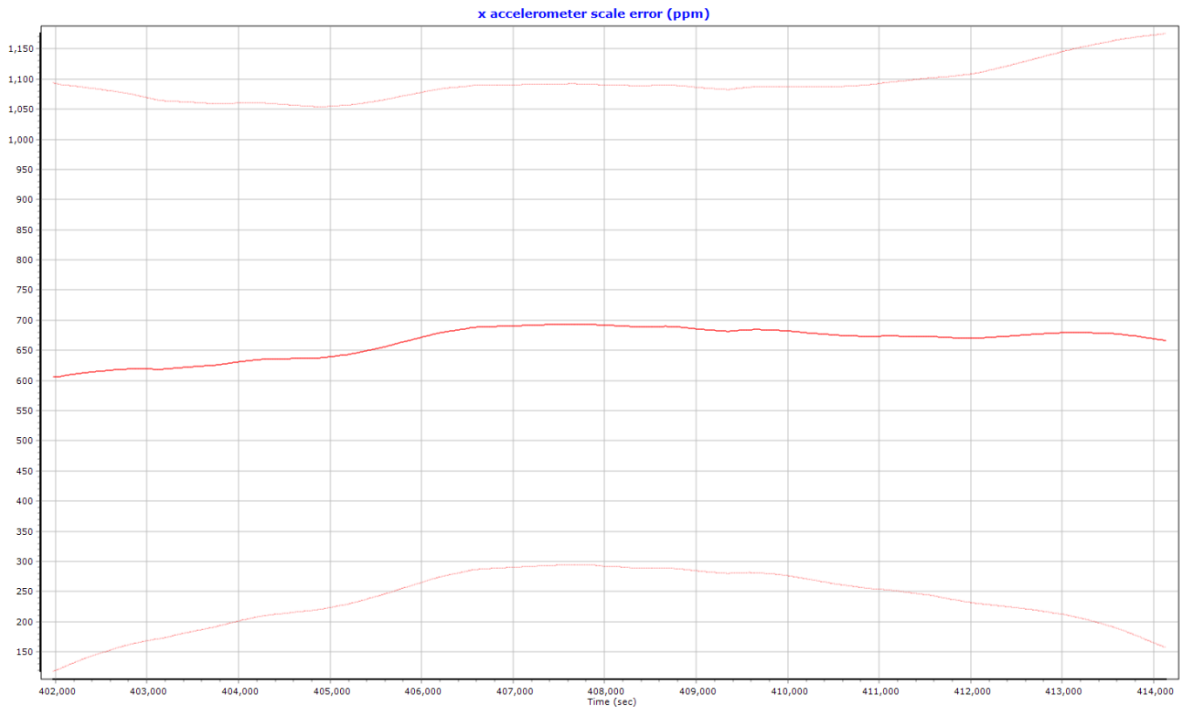
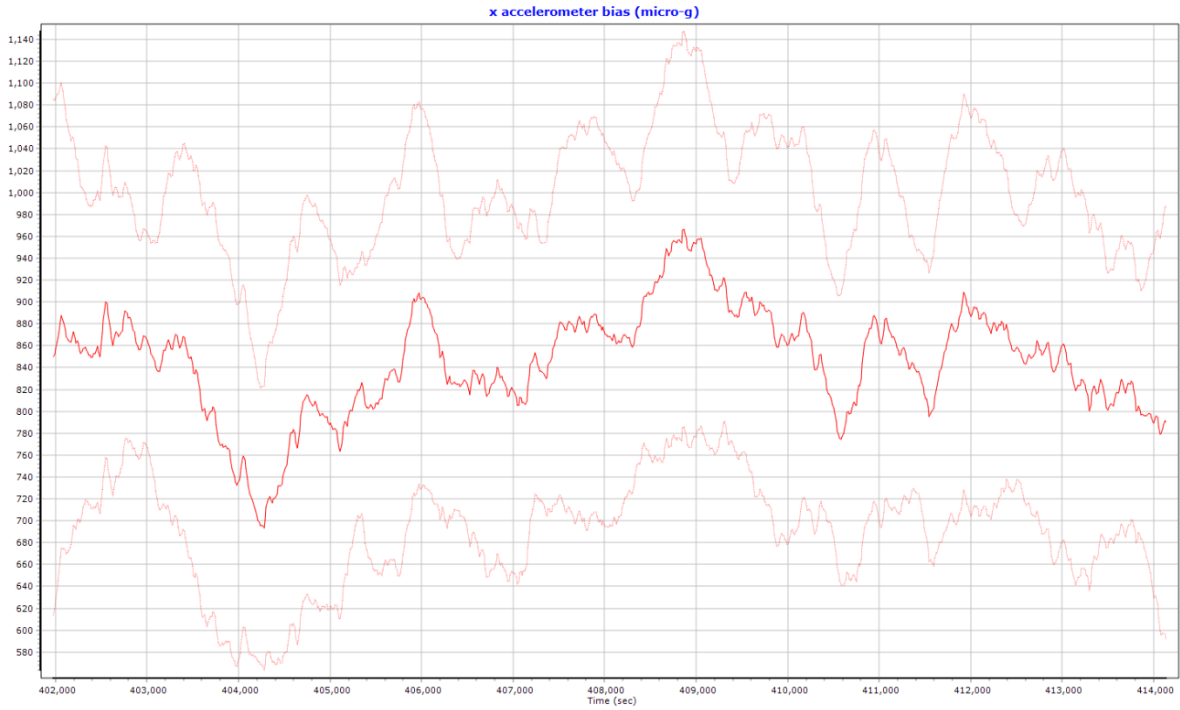
End:

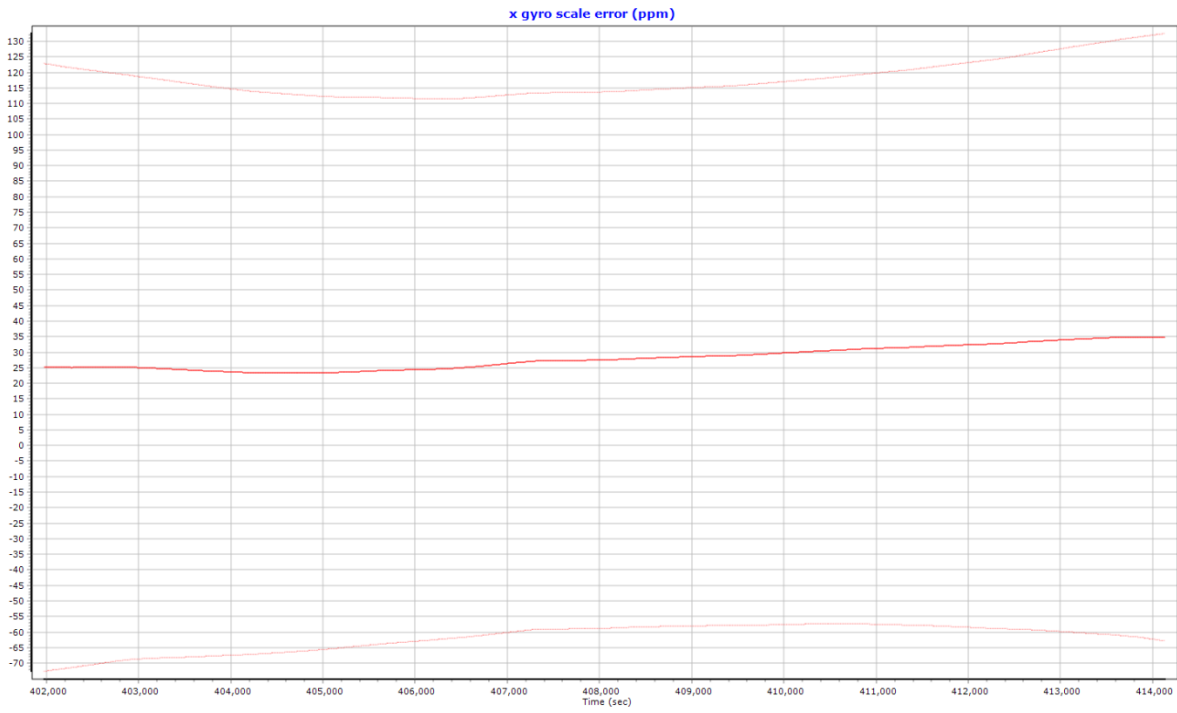
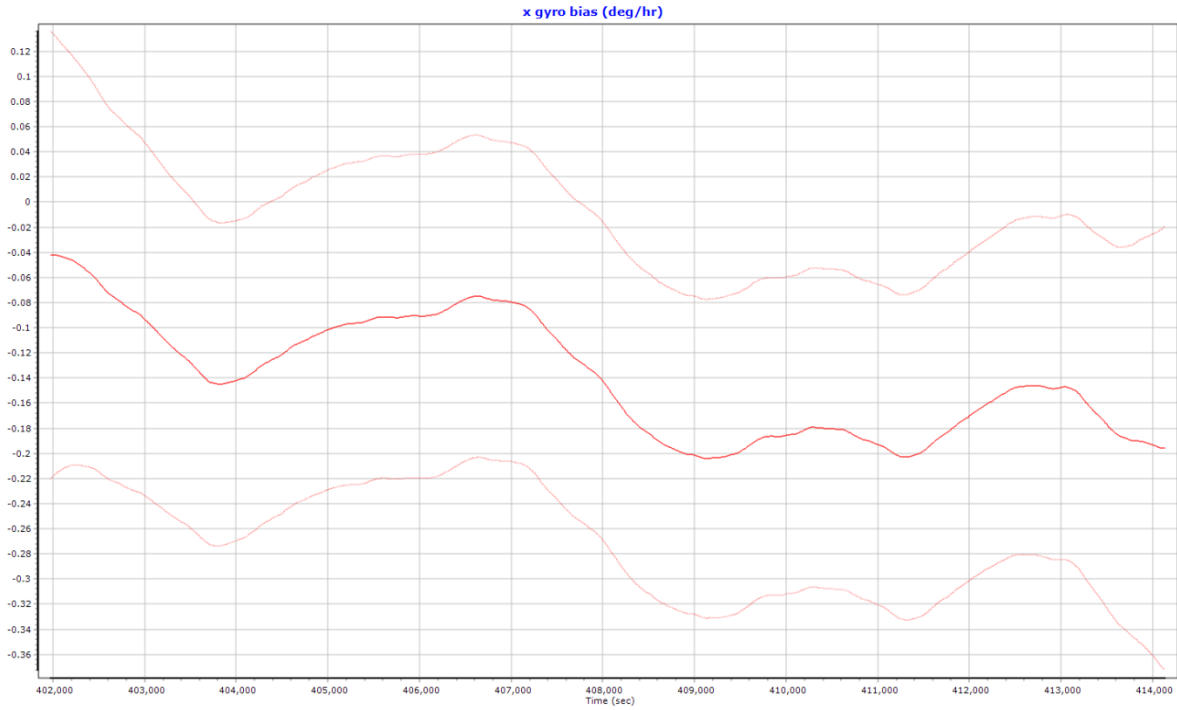
Entire time interval

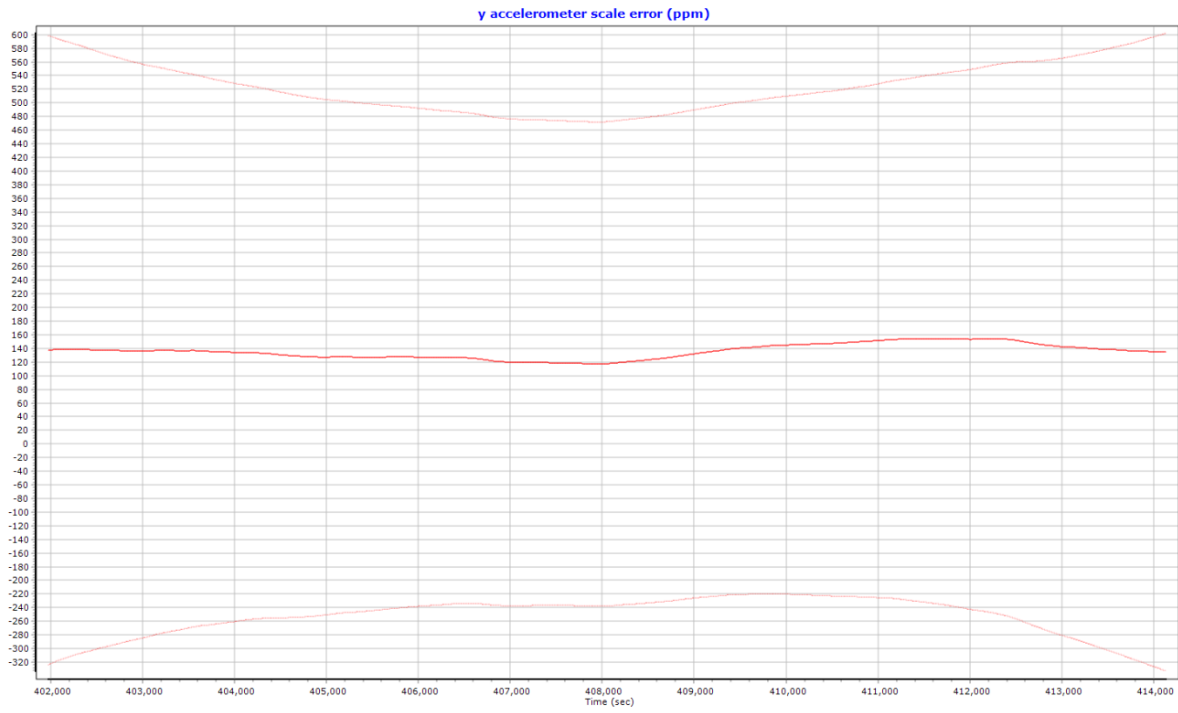
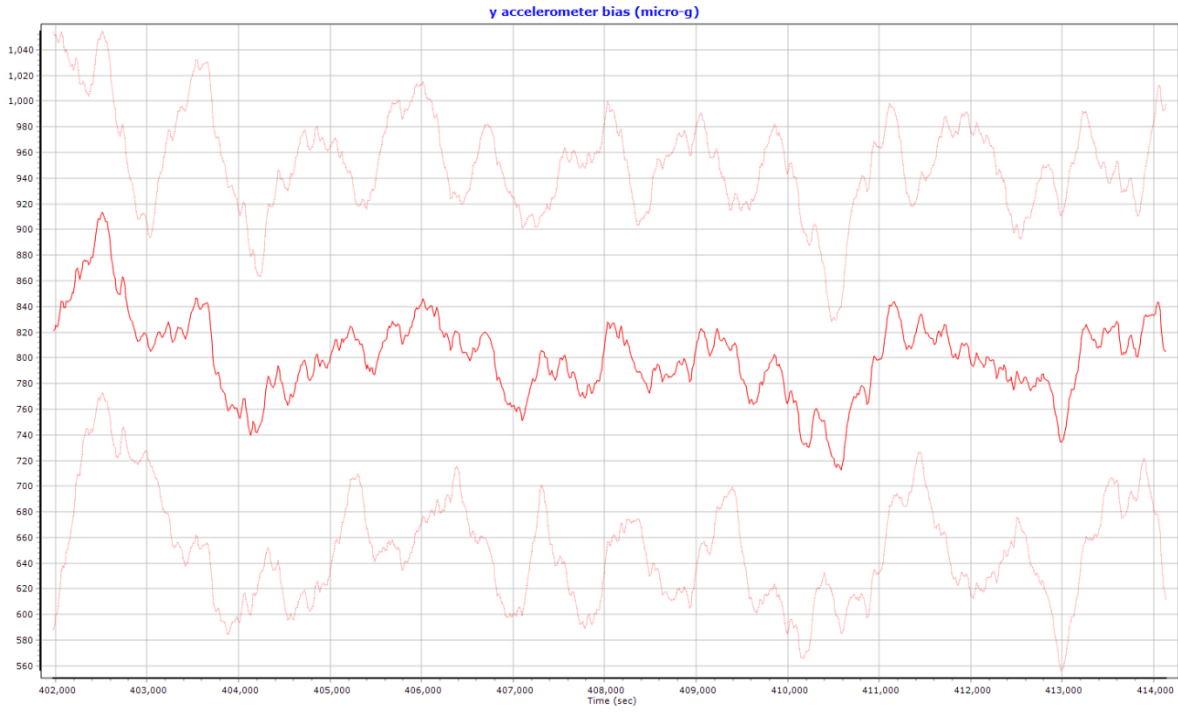
Seconds of start week

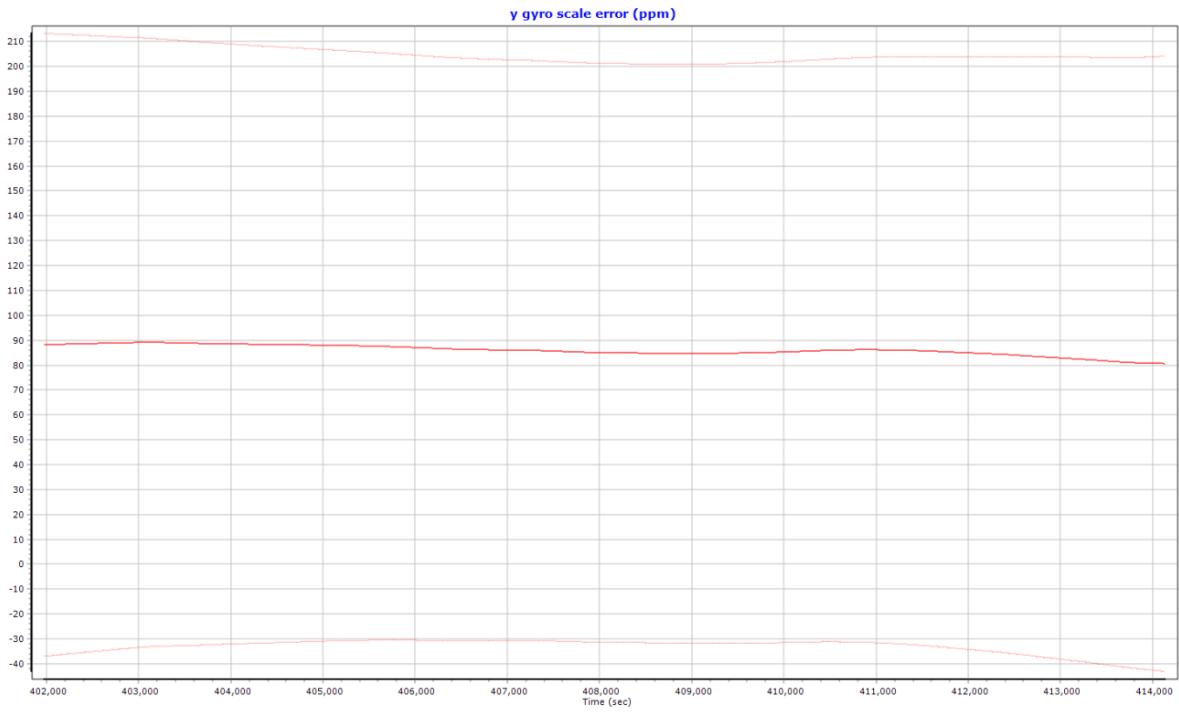
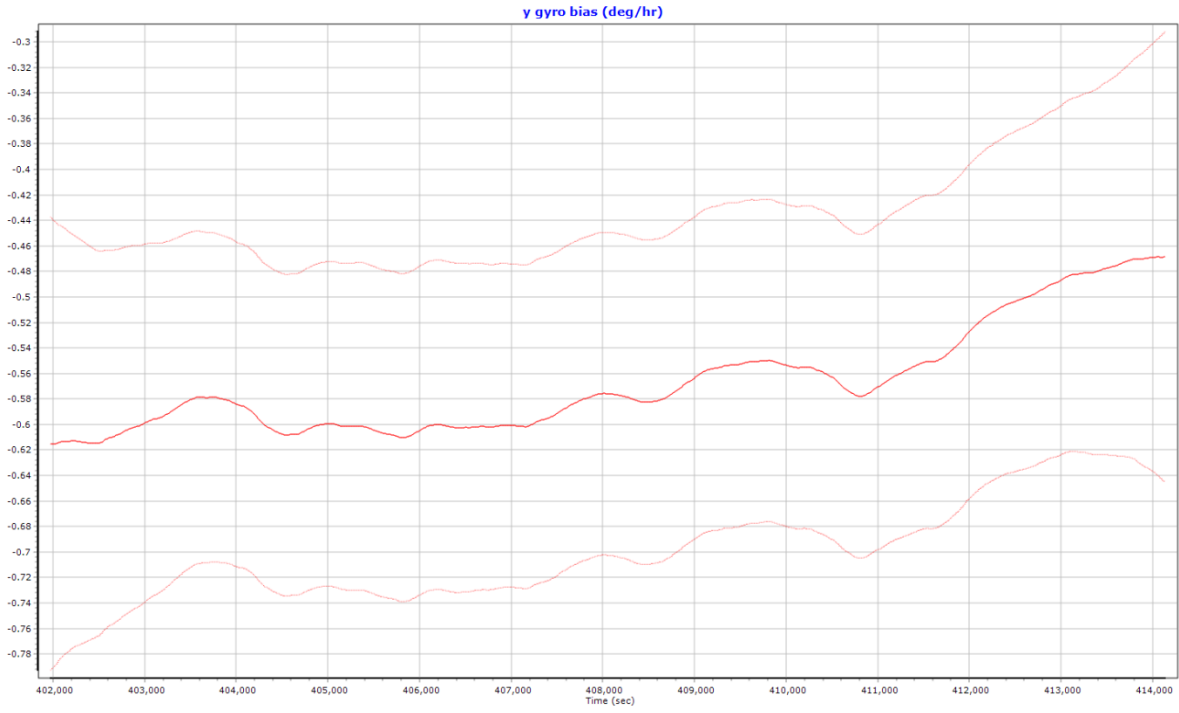
UTC Offset:

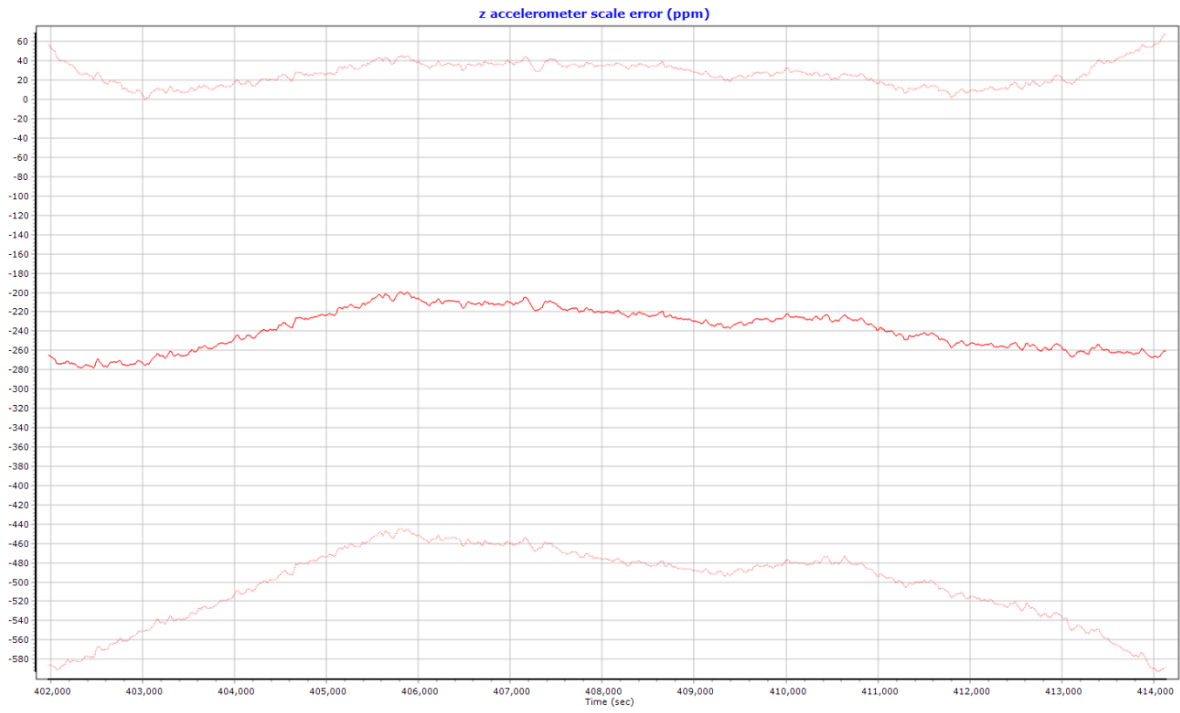
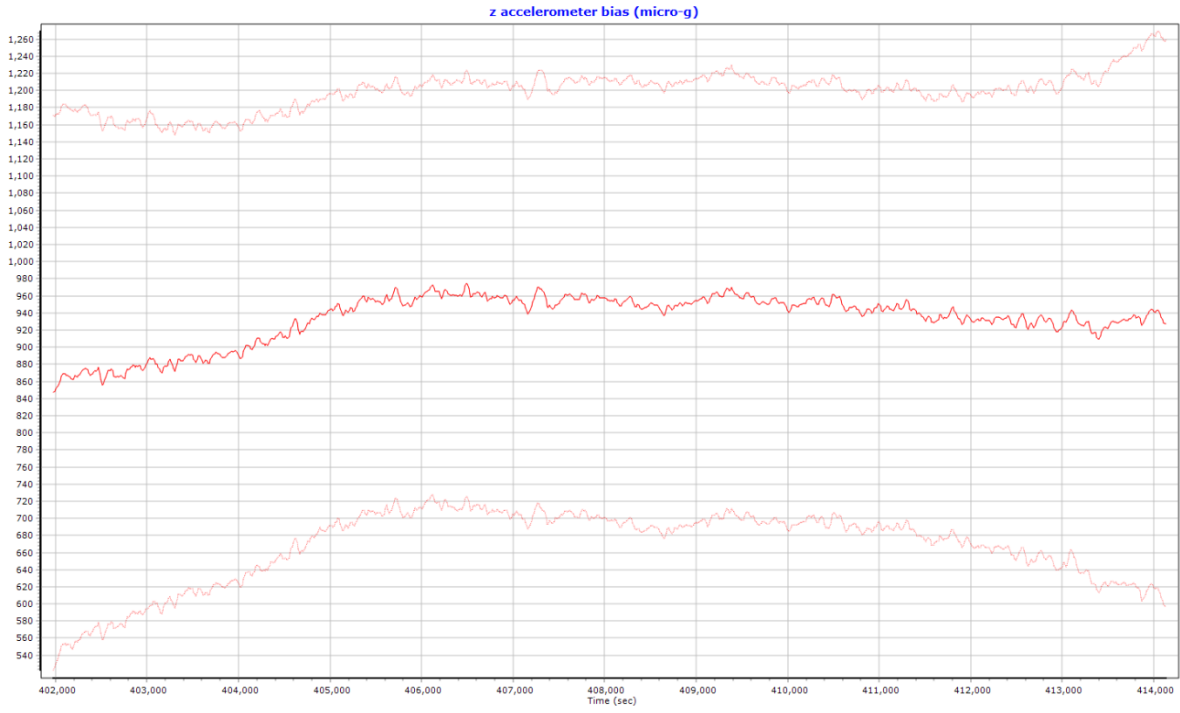
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

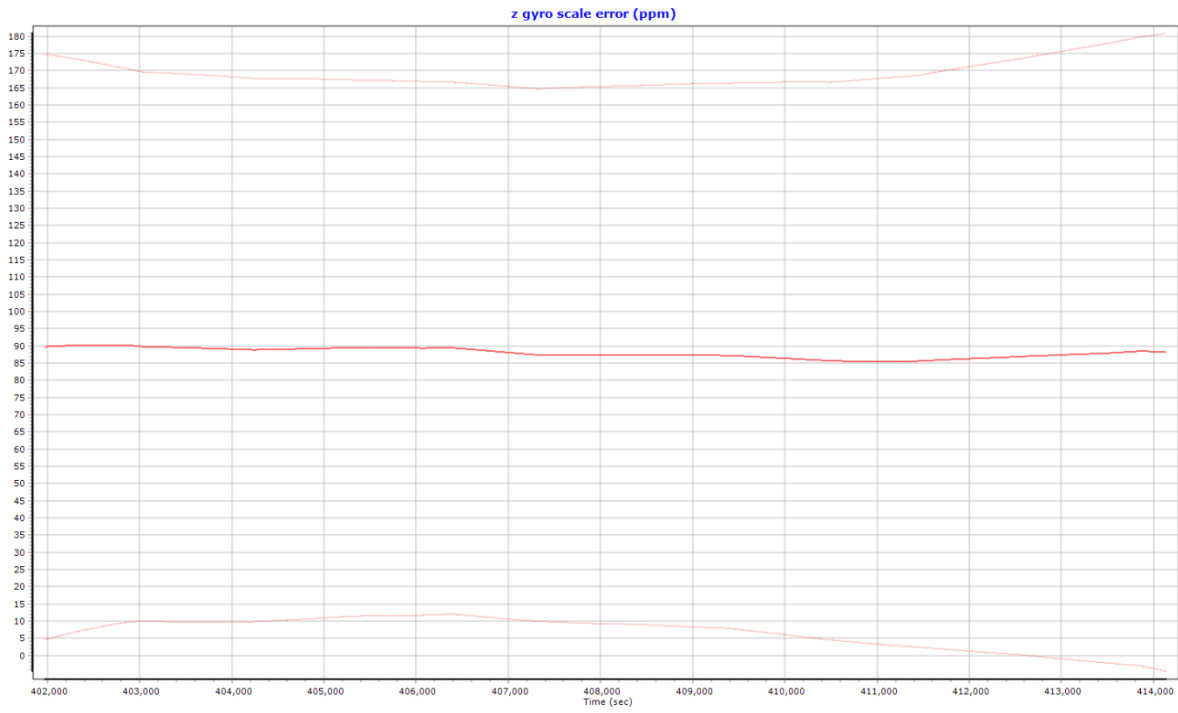
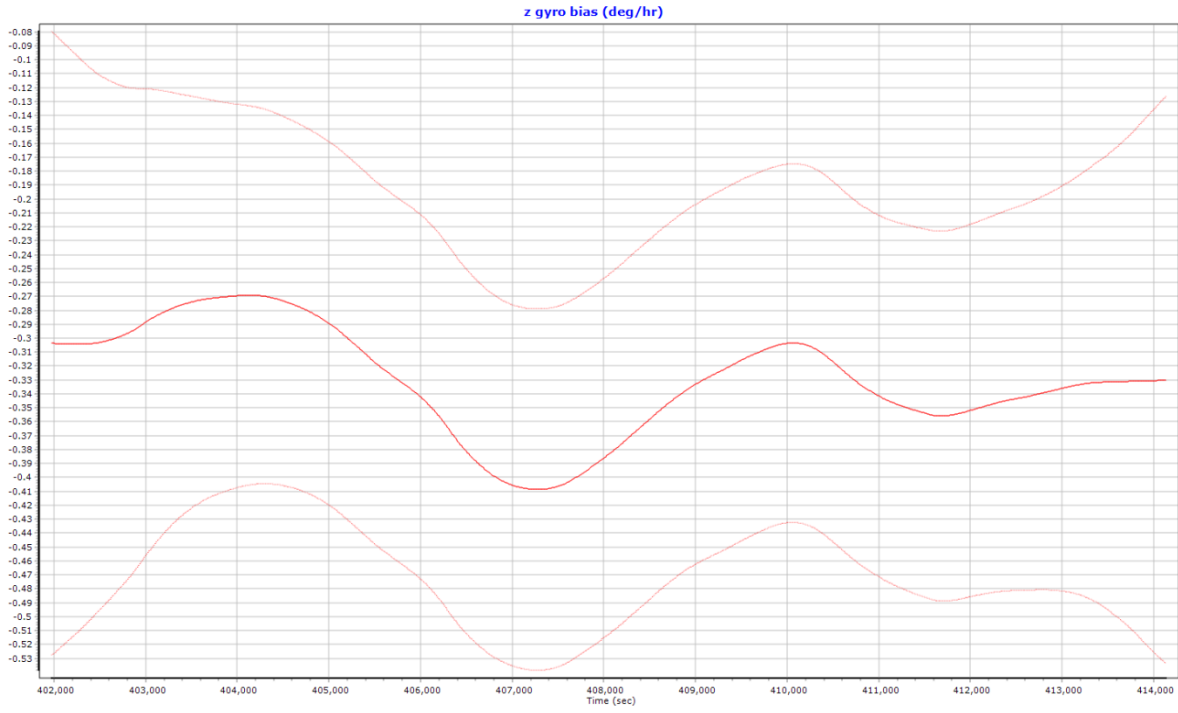




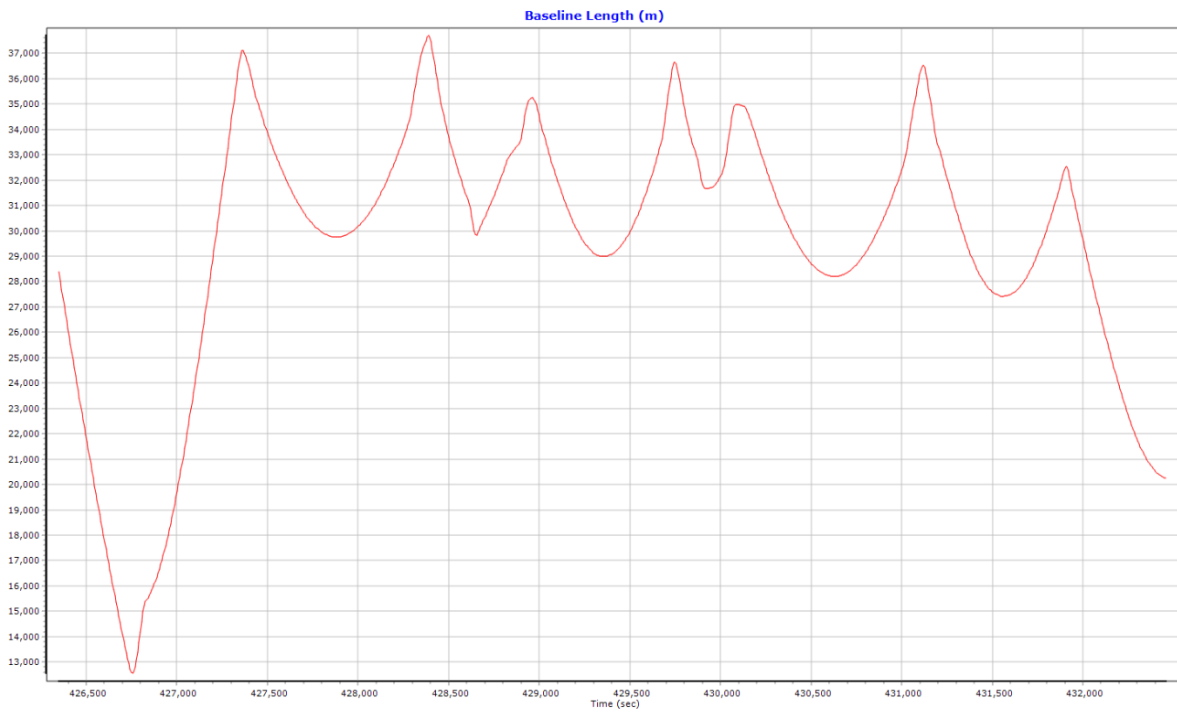
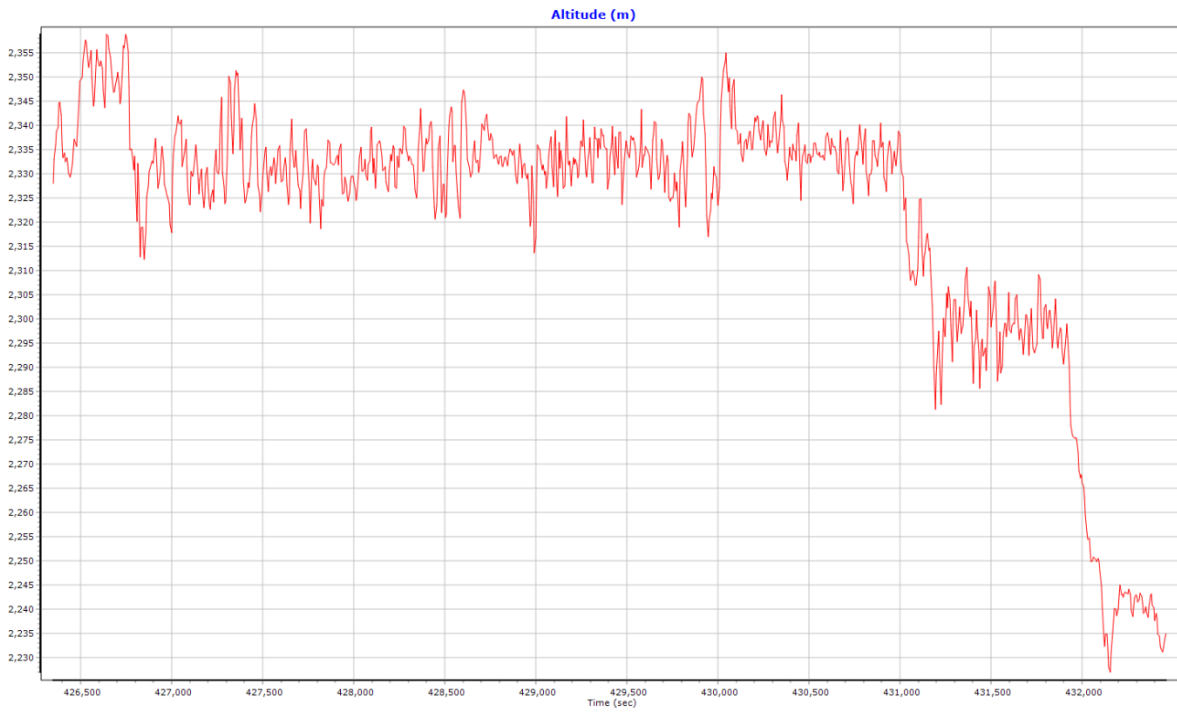


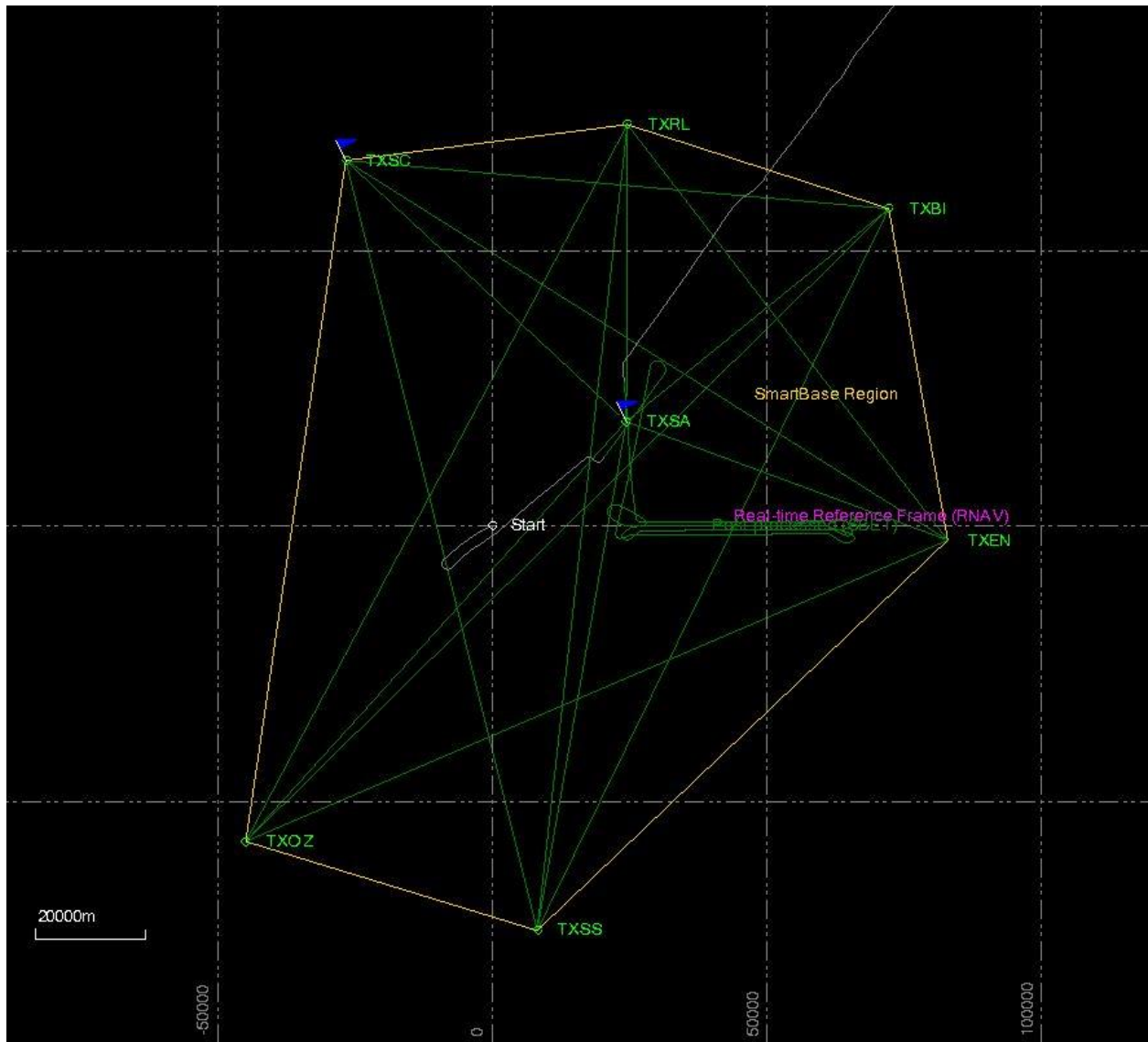






UNB18060B







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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

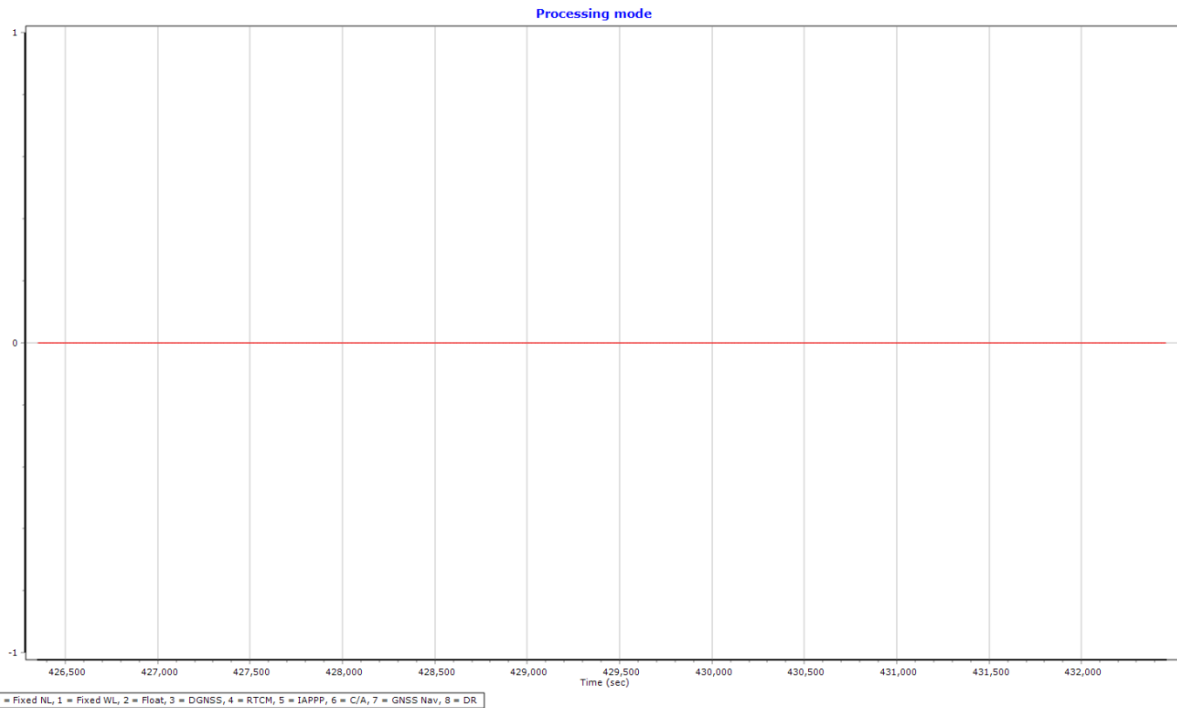
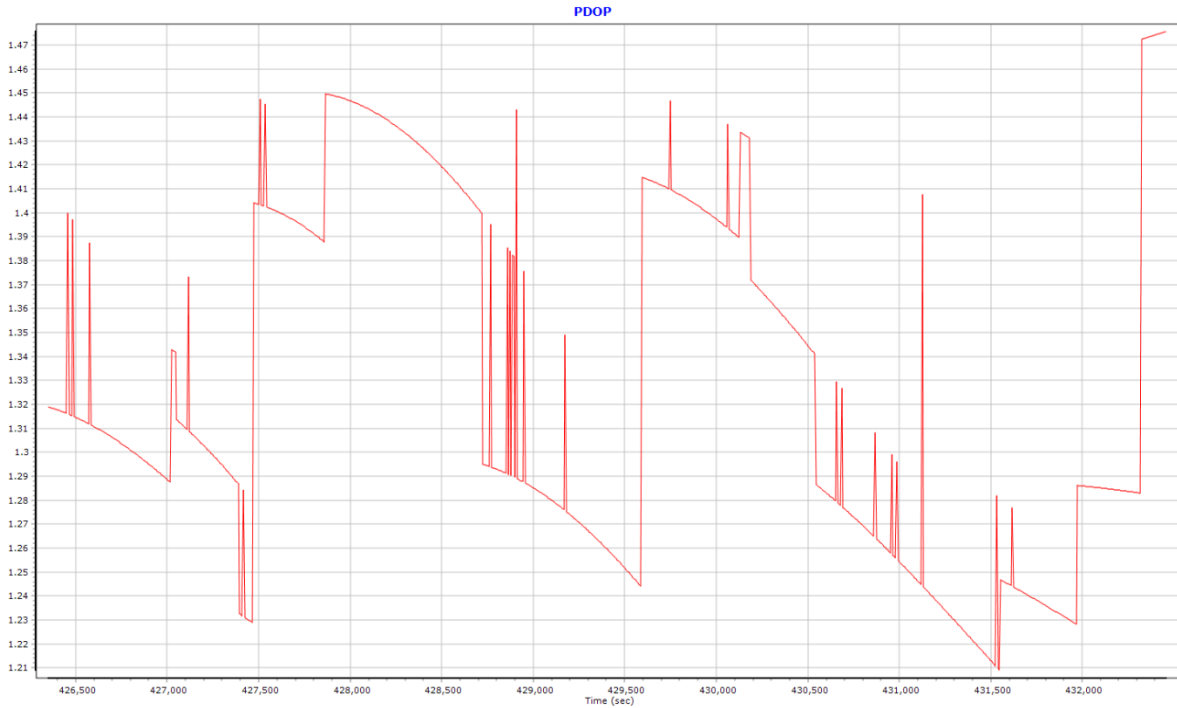
Standard Deviation:

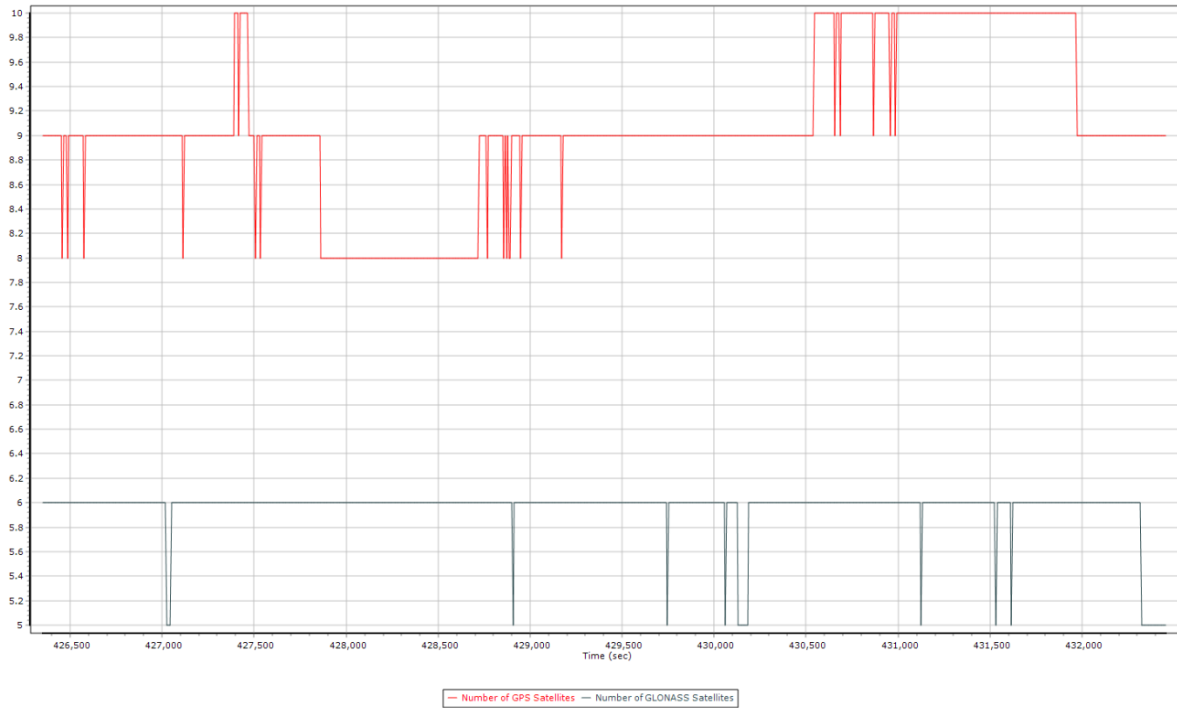
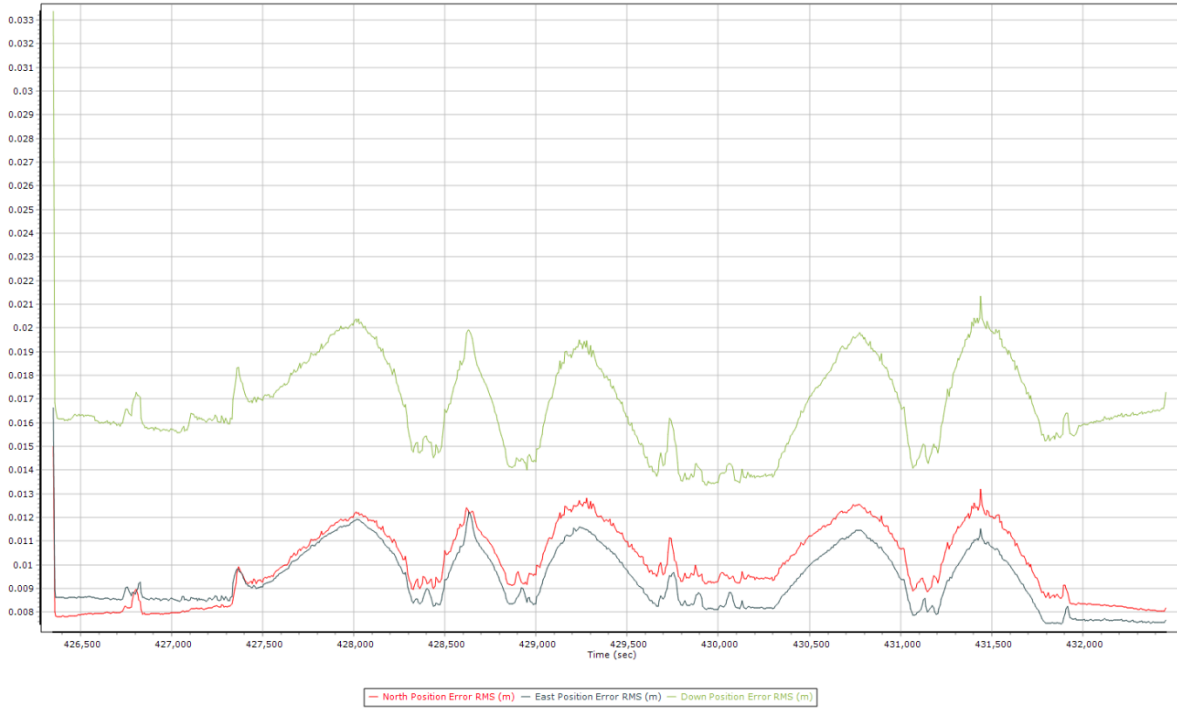
Aircraft to Reference Mounting Angles

X:

Y:

Z:





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

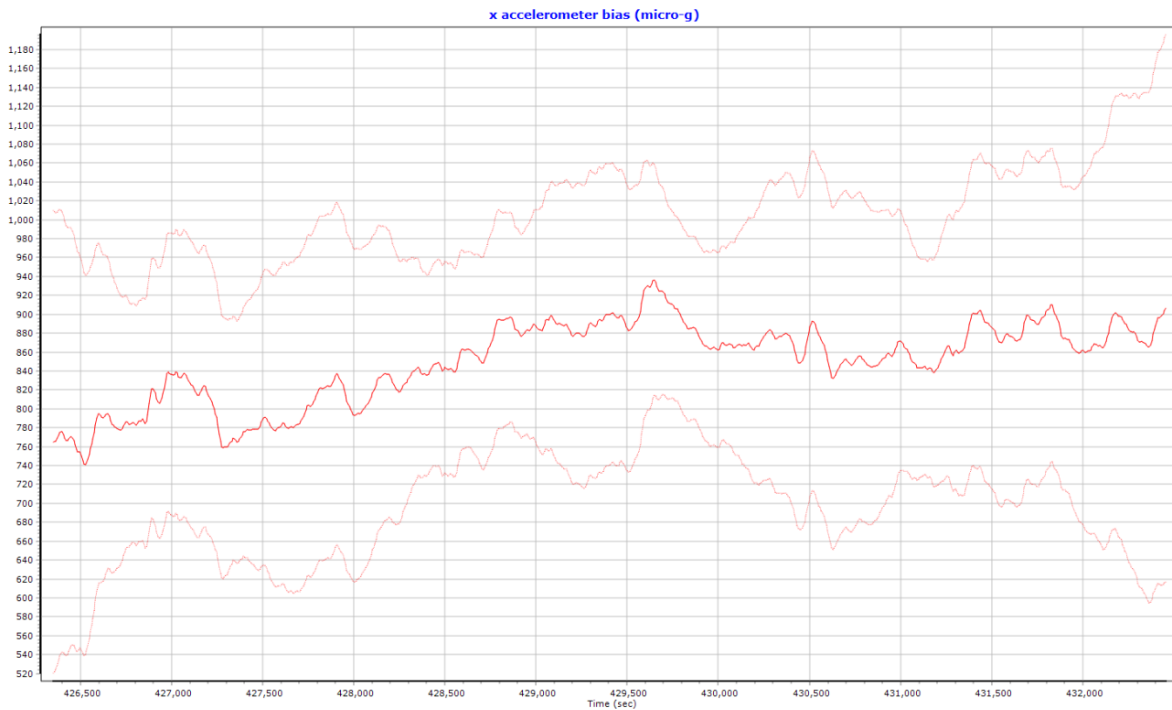
Start: 426349.288
End: 432467.507

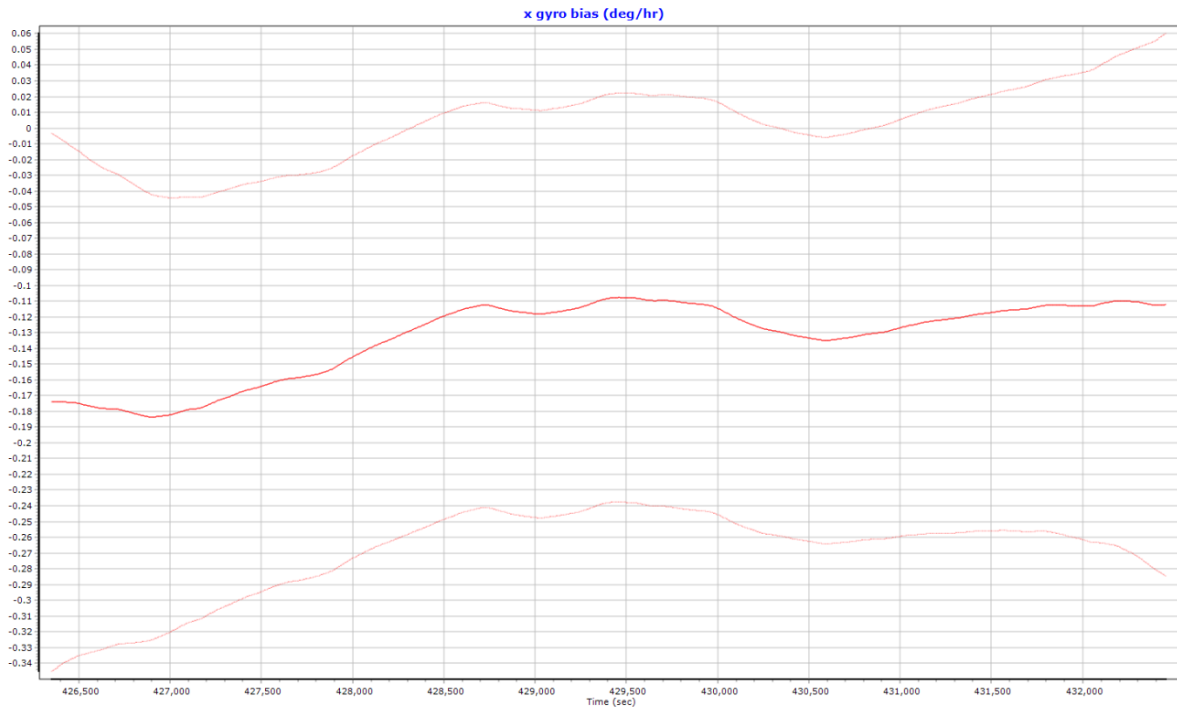
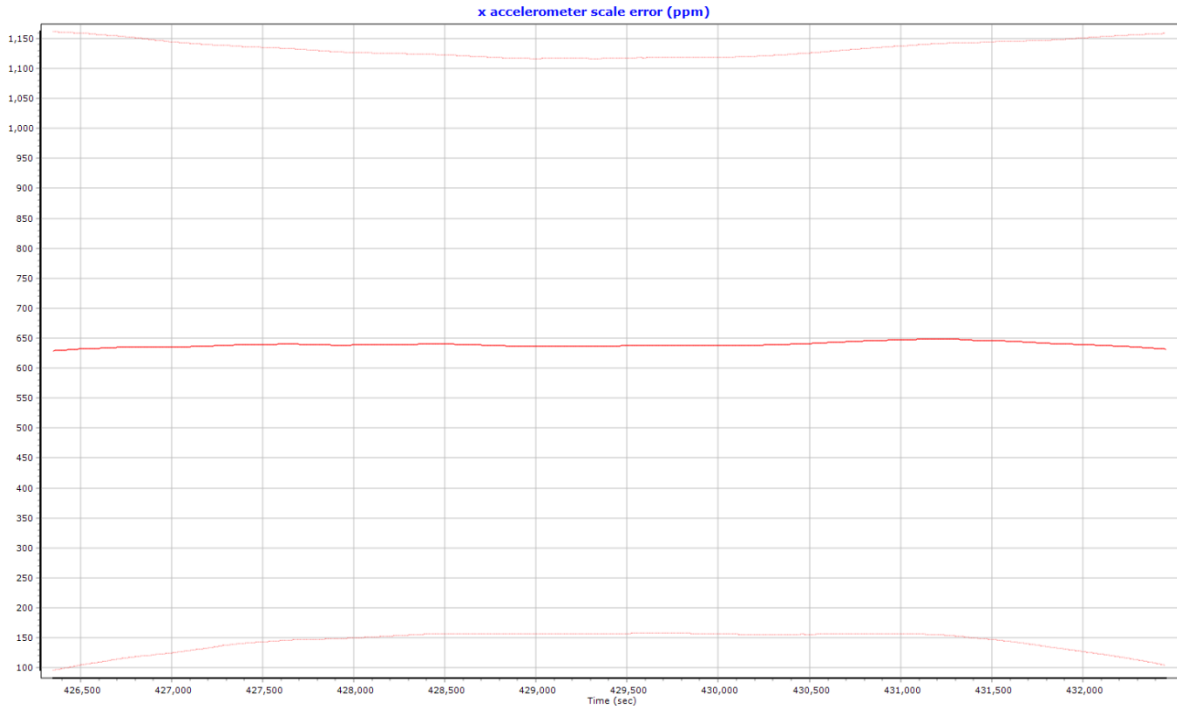
Entire time interval
 Seconds of start week

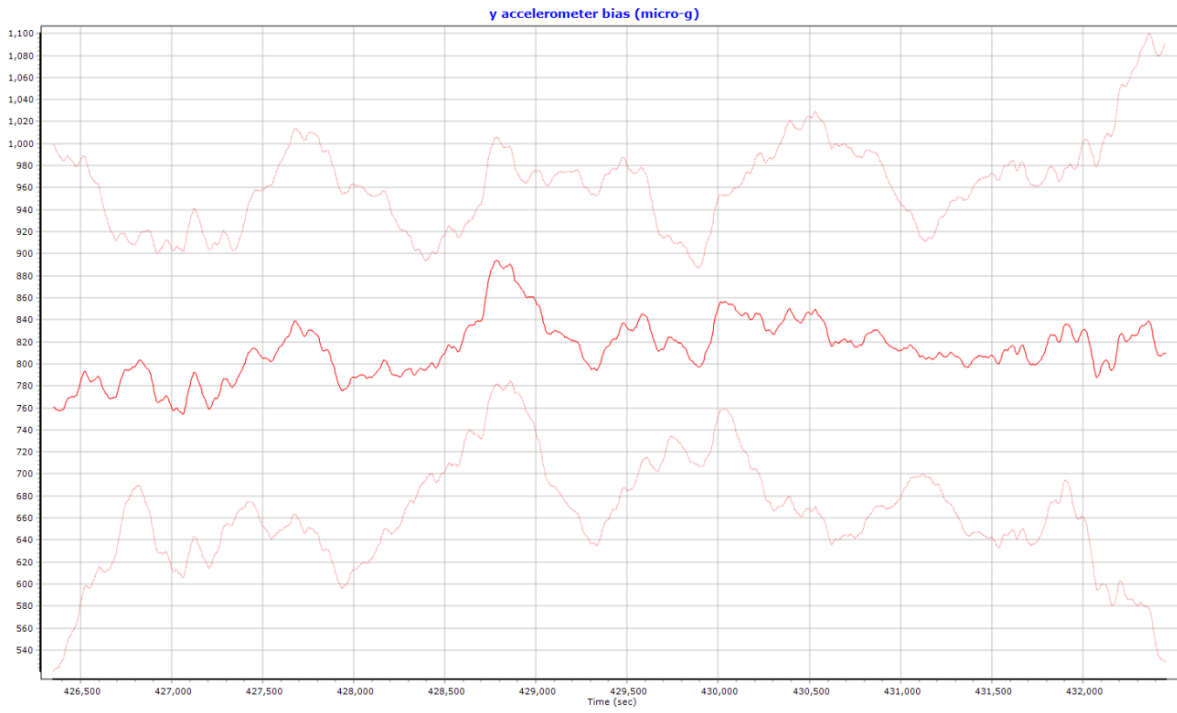
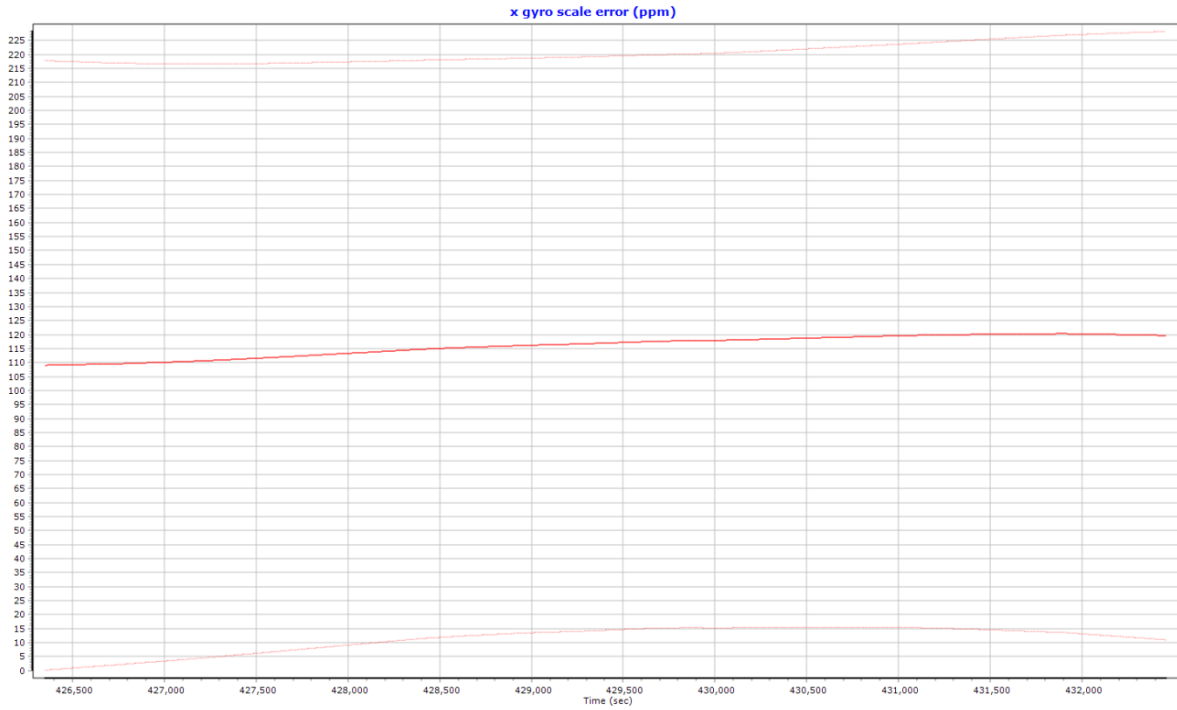
UTC Offset: 18.000

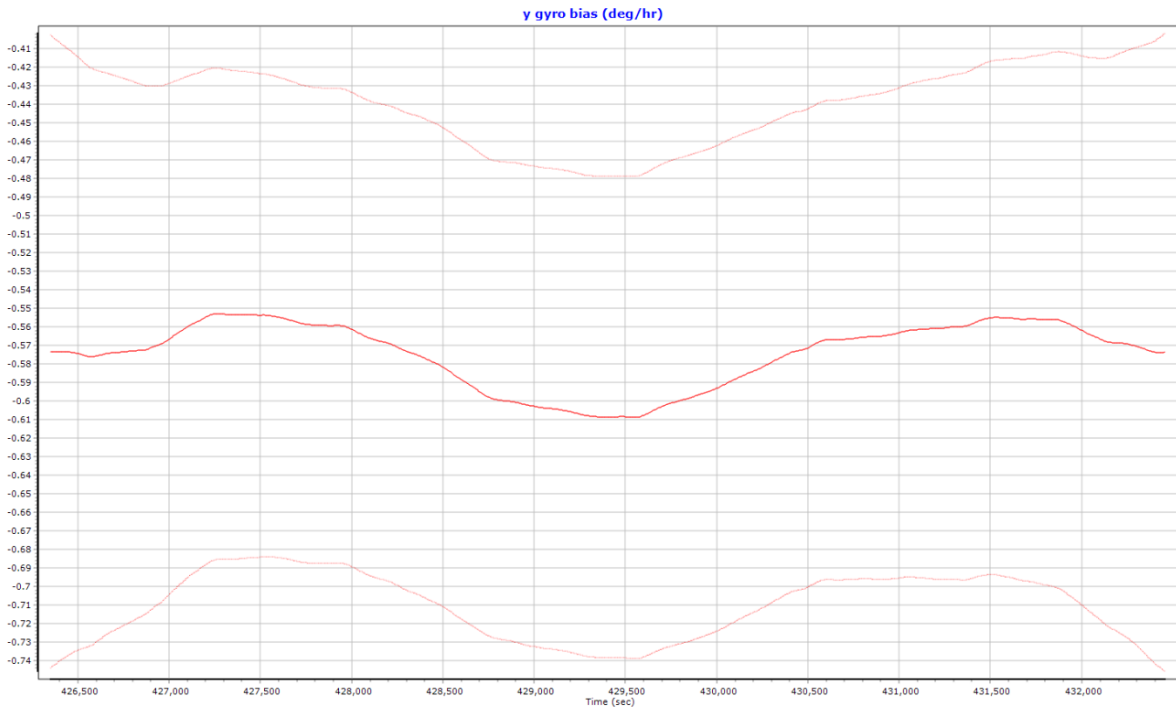
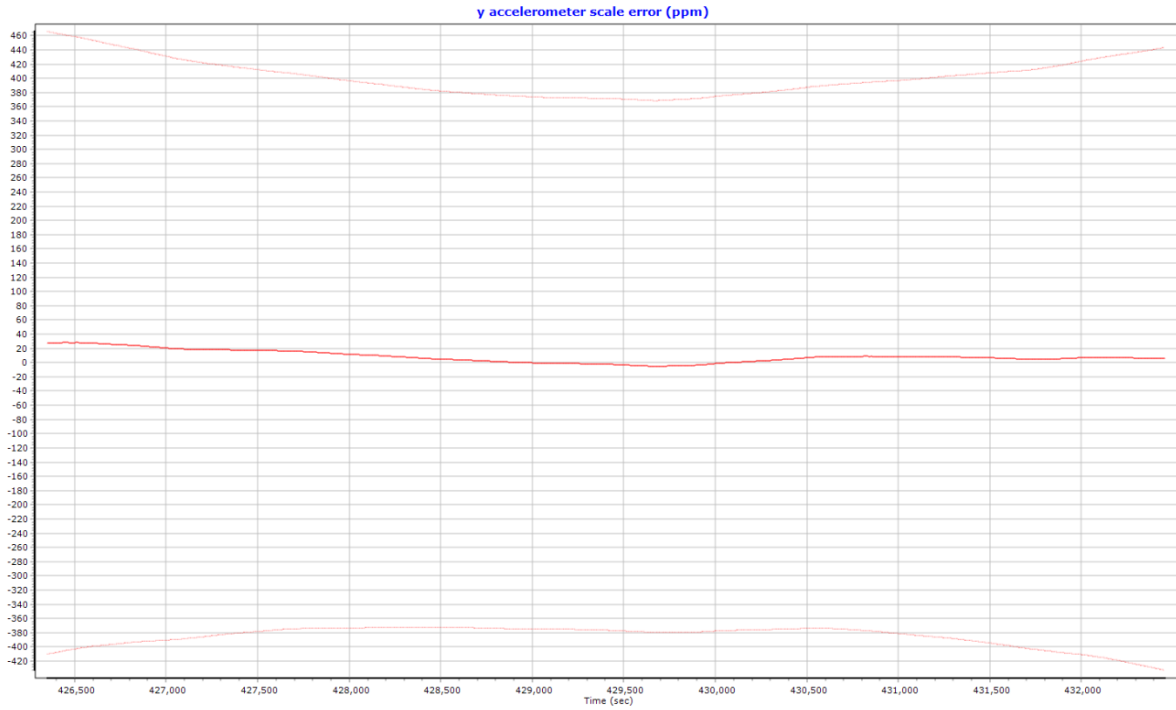
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

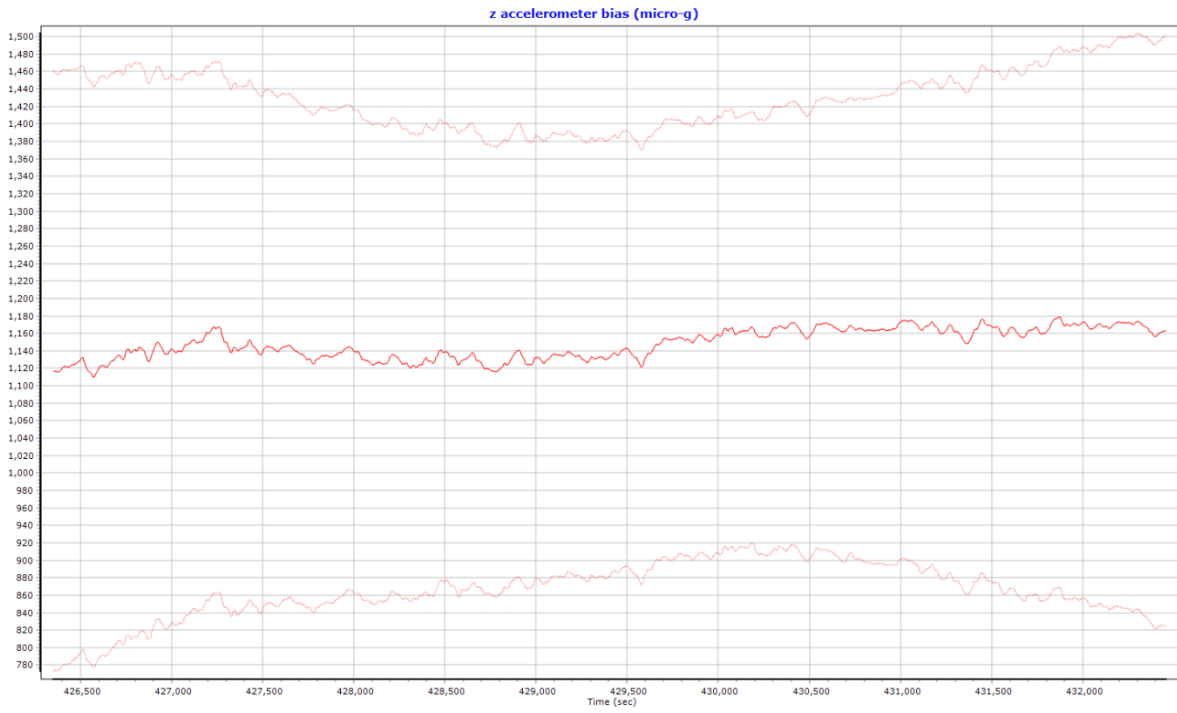
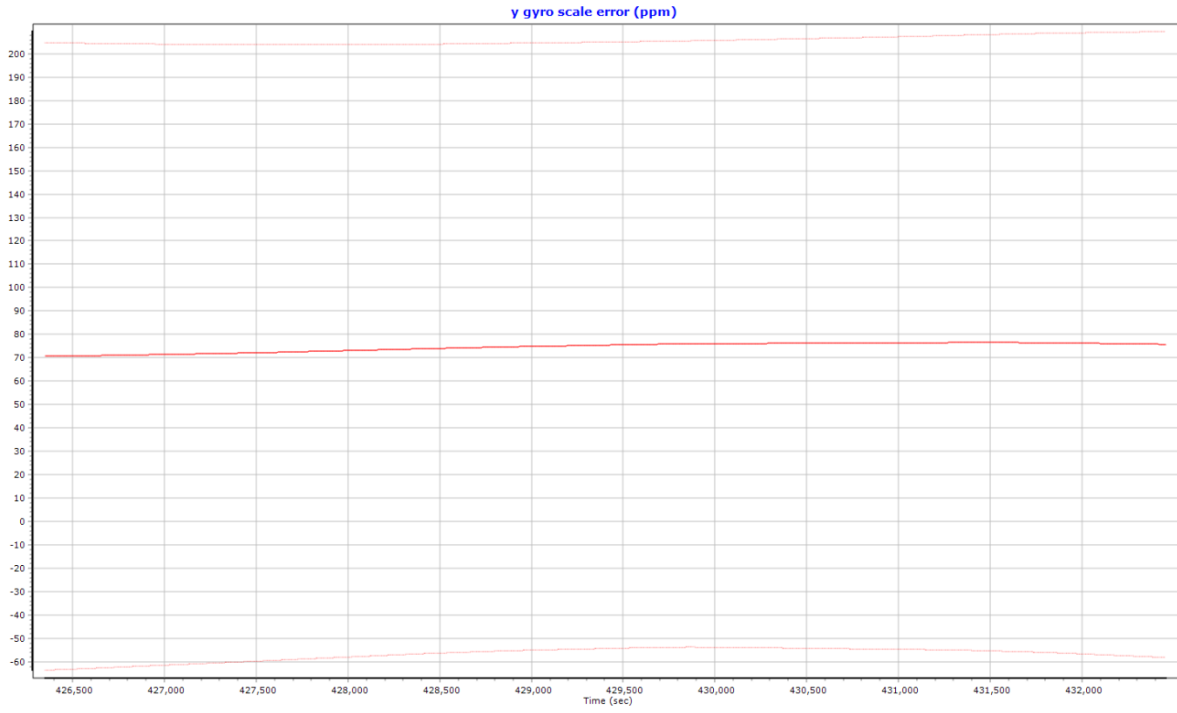
OK Cancel

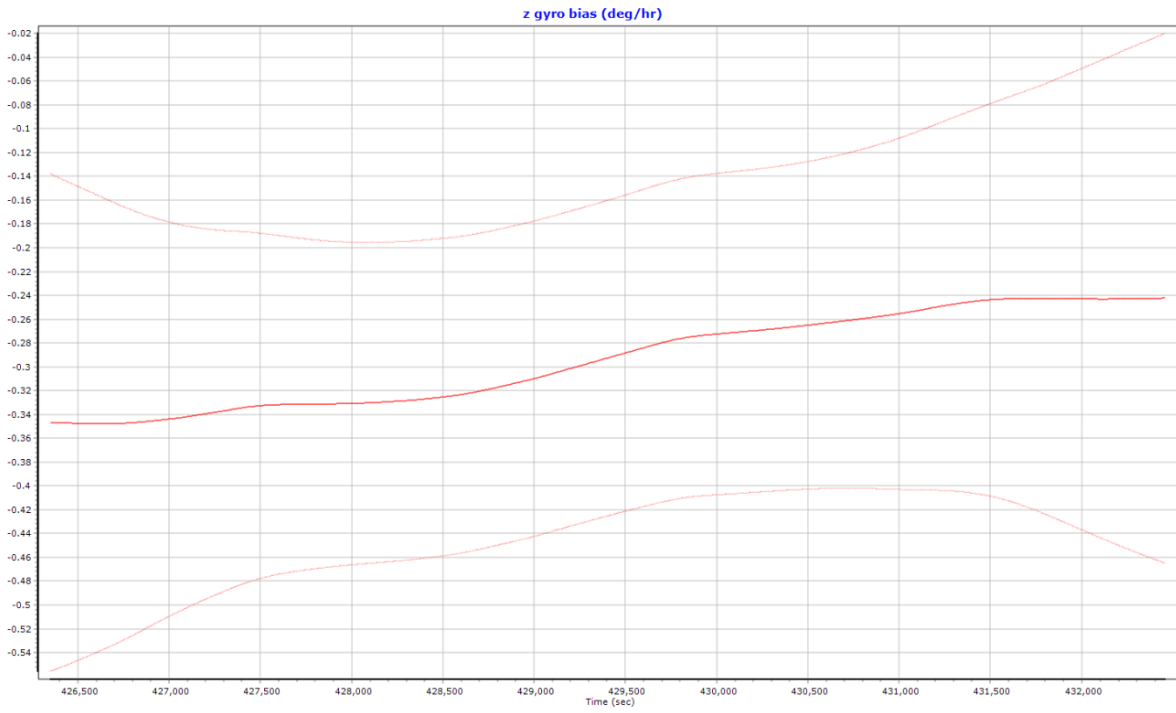
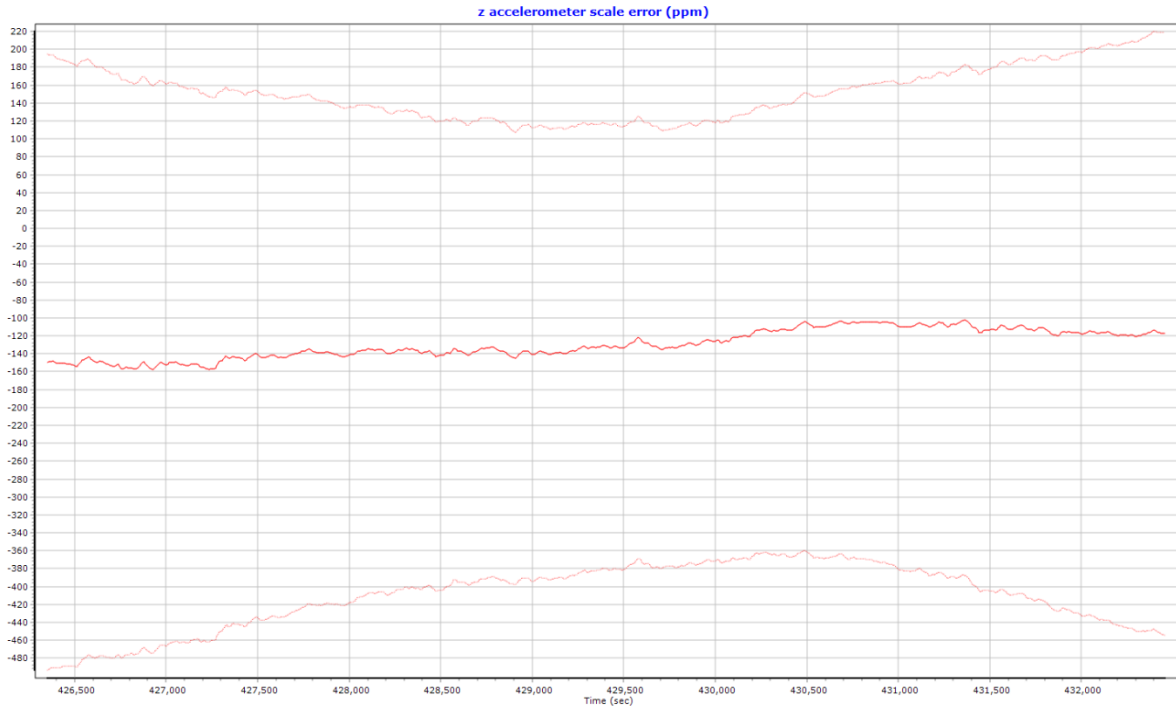


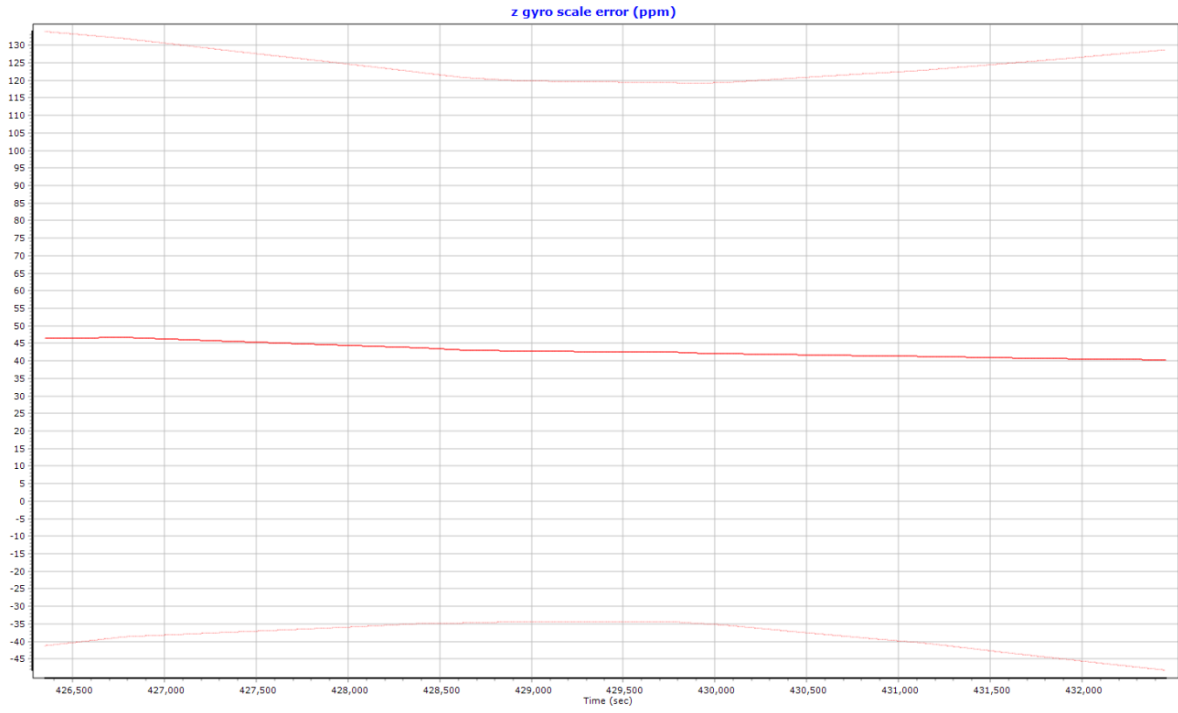




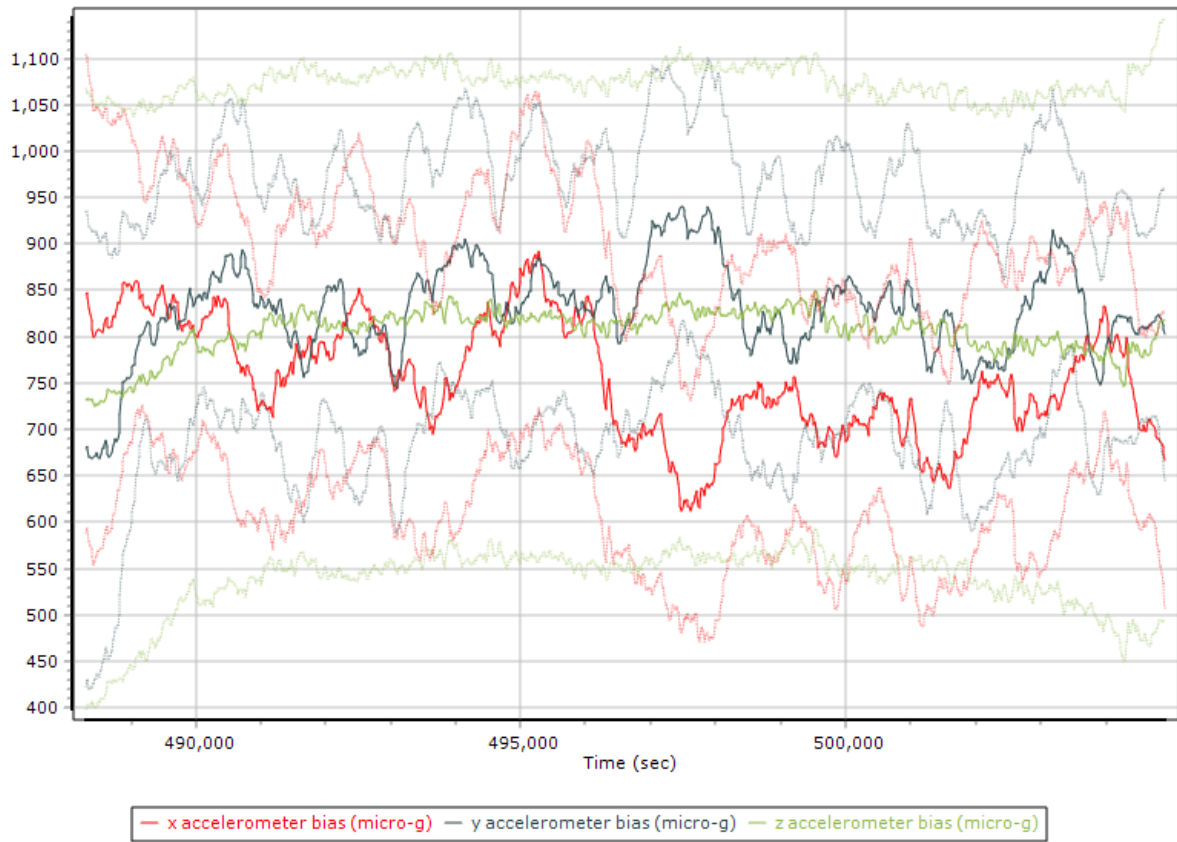


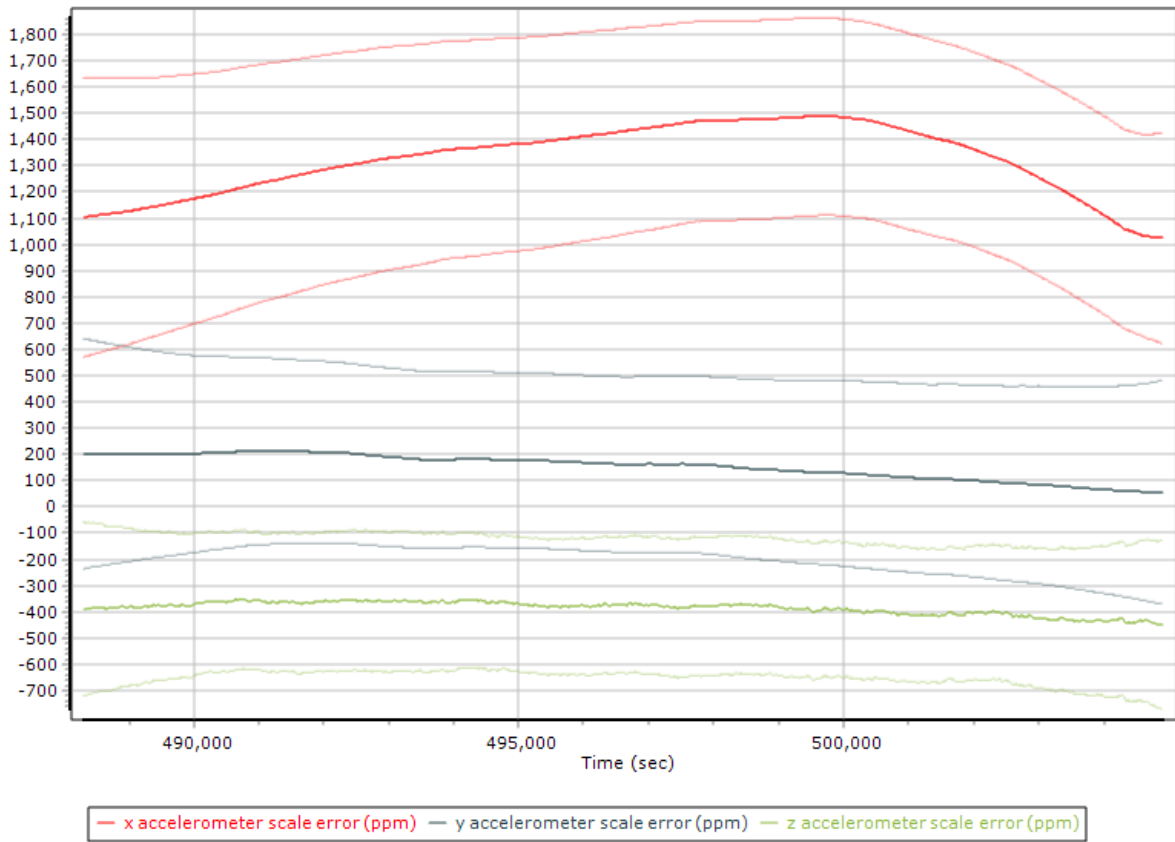


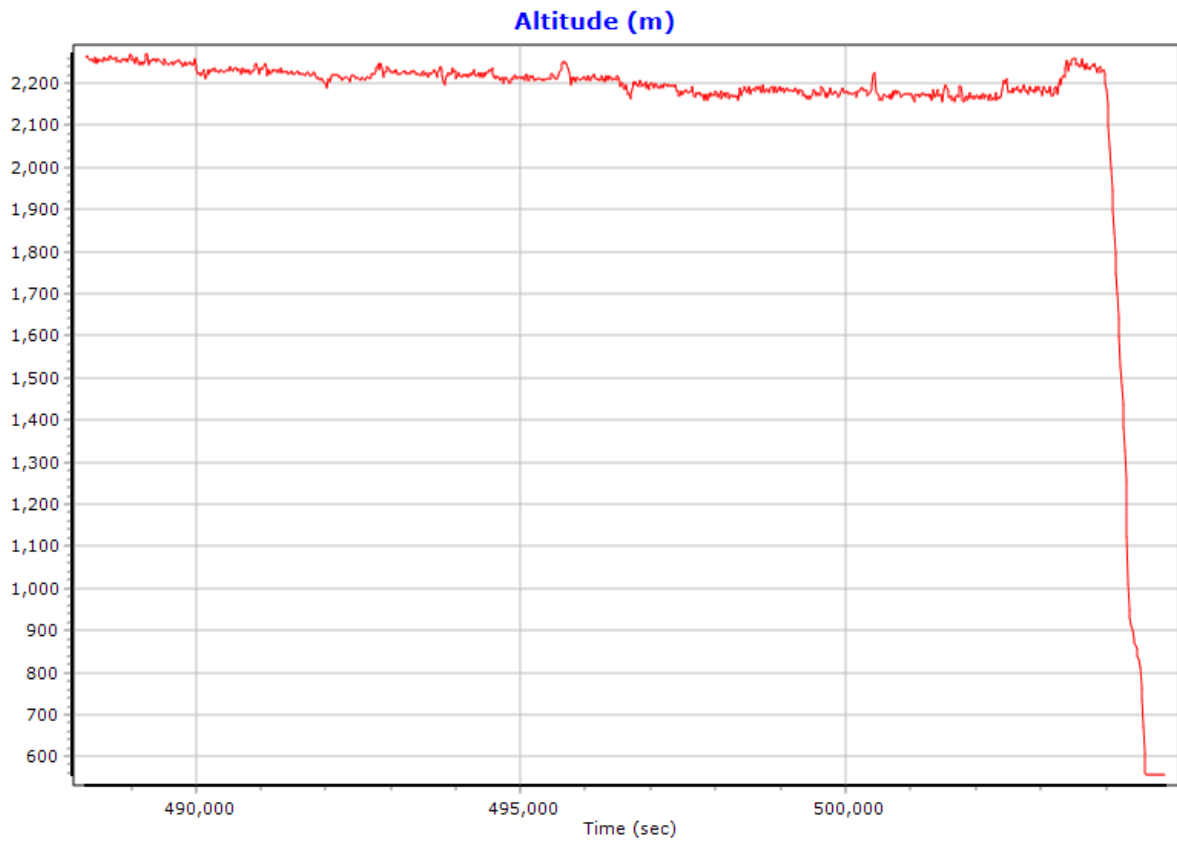


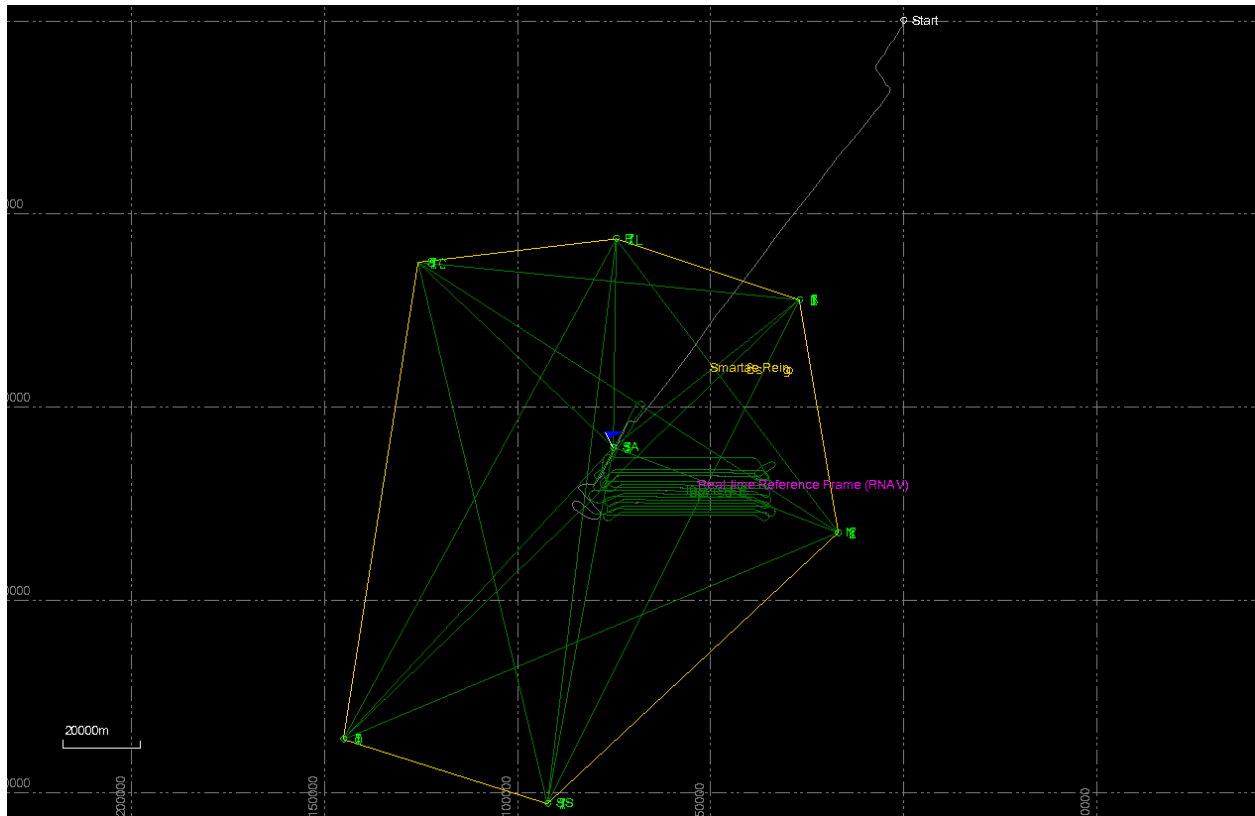
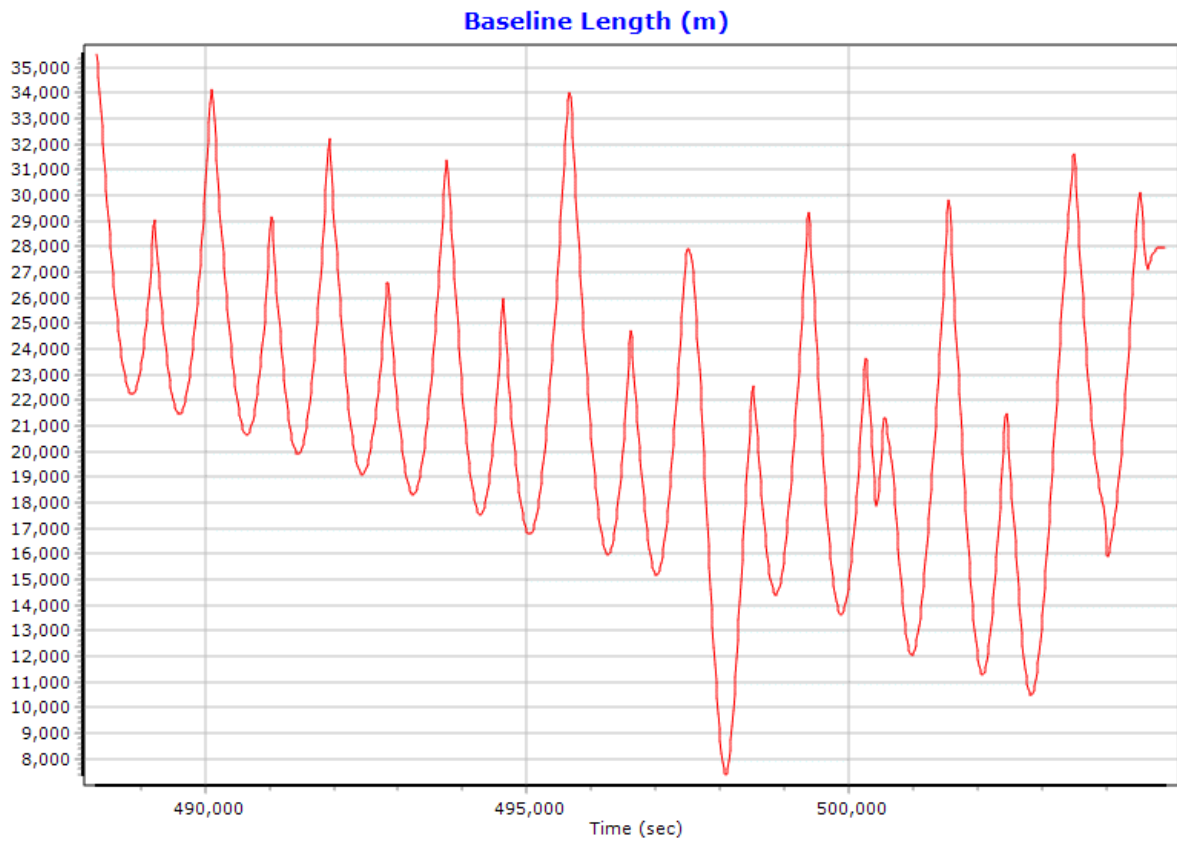


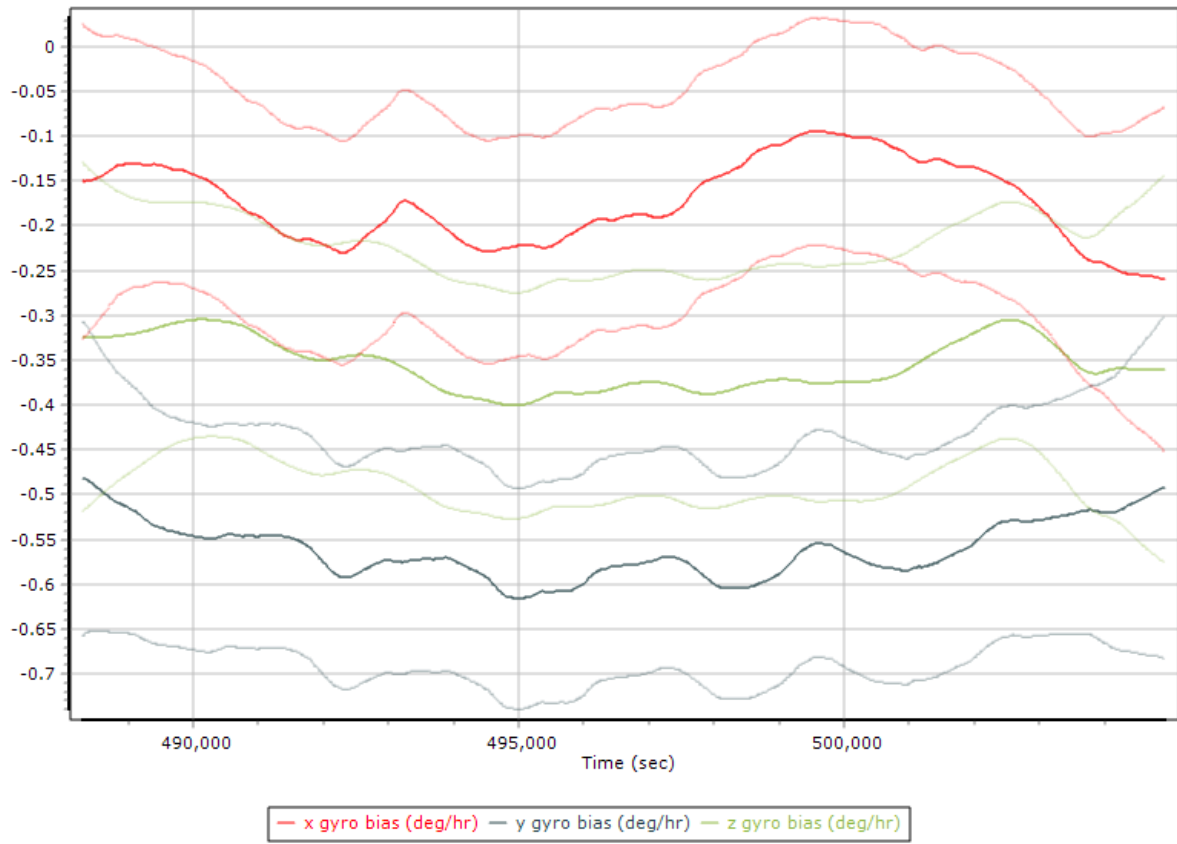
UNB18061A

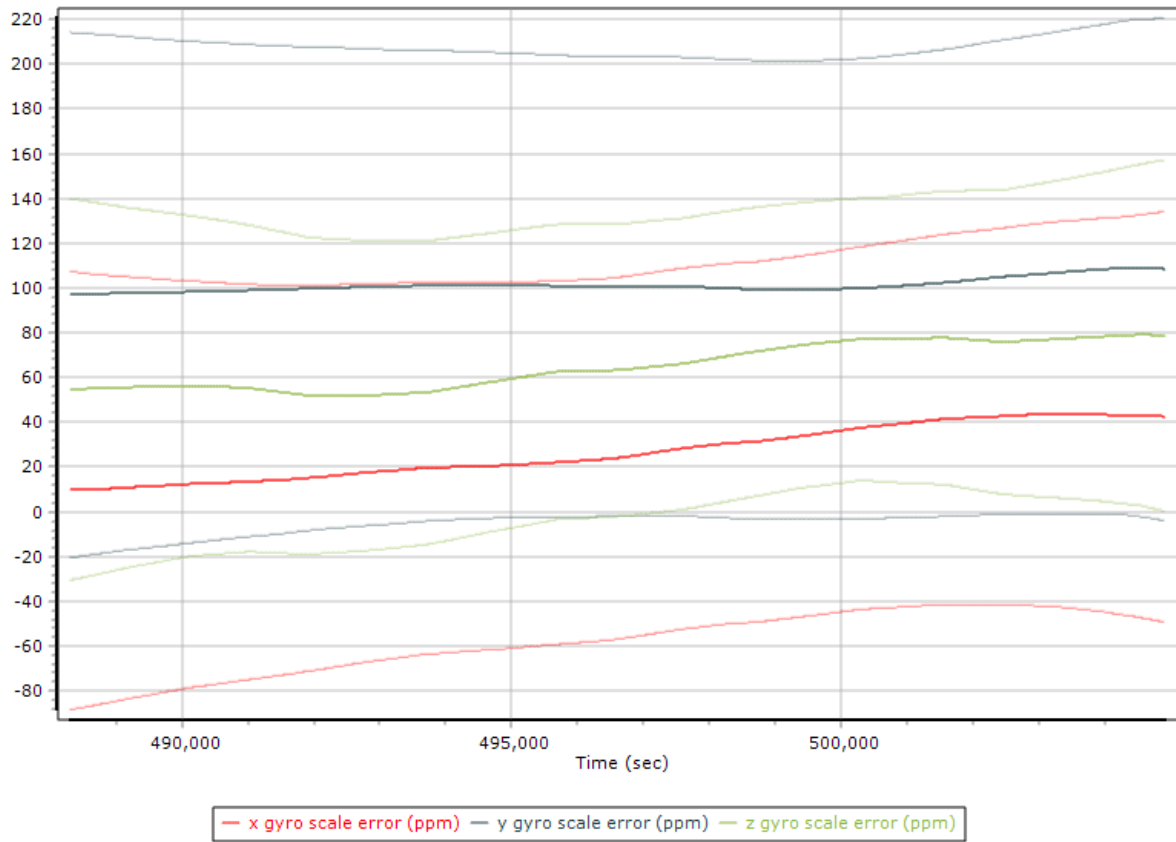












Project Settings [X]

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

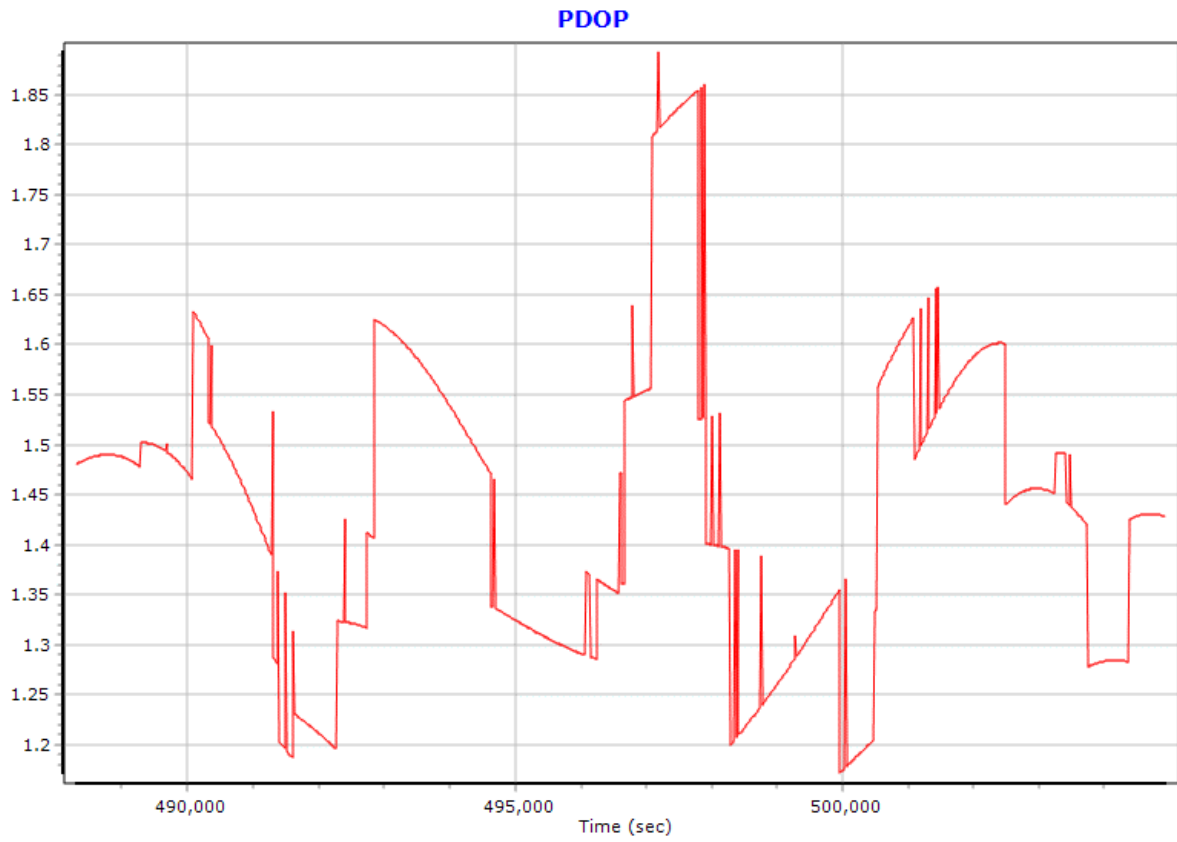
Aircraft to Reference Mounting Angles

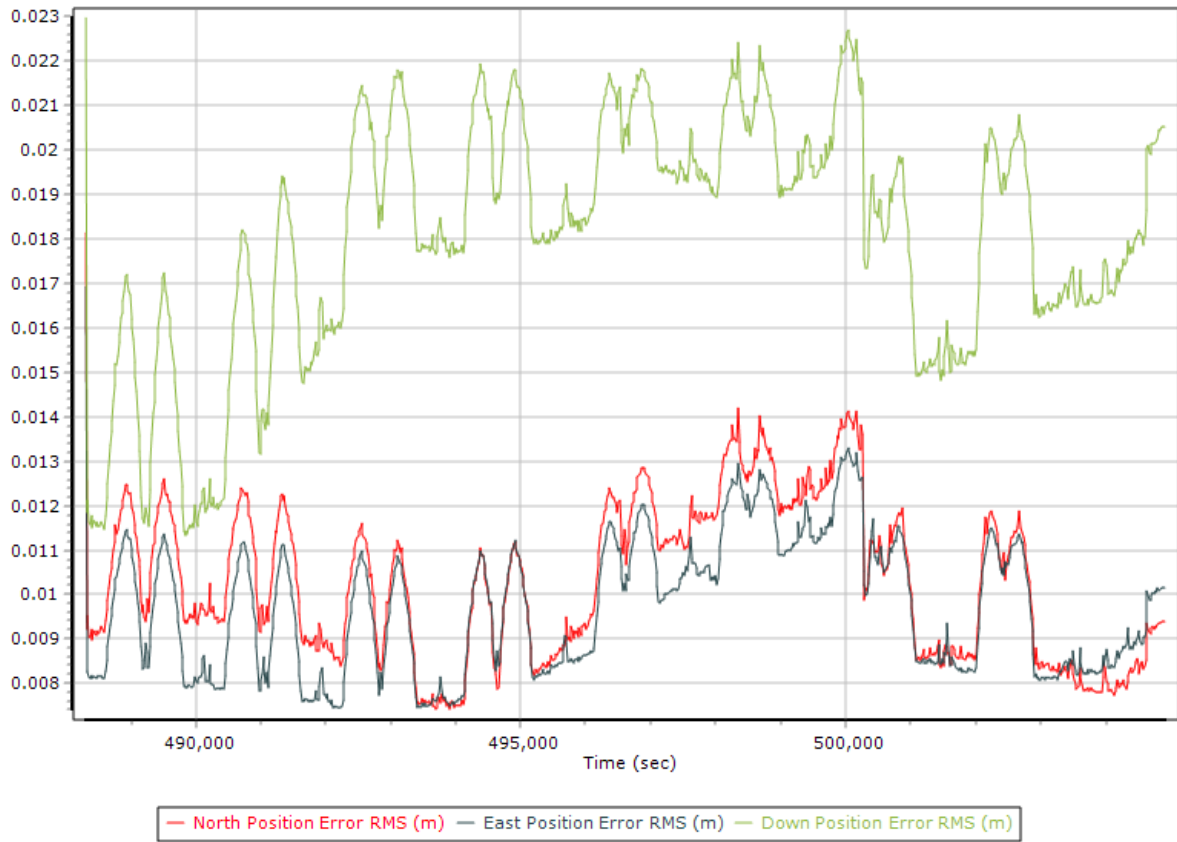
X:

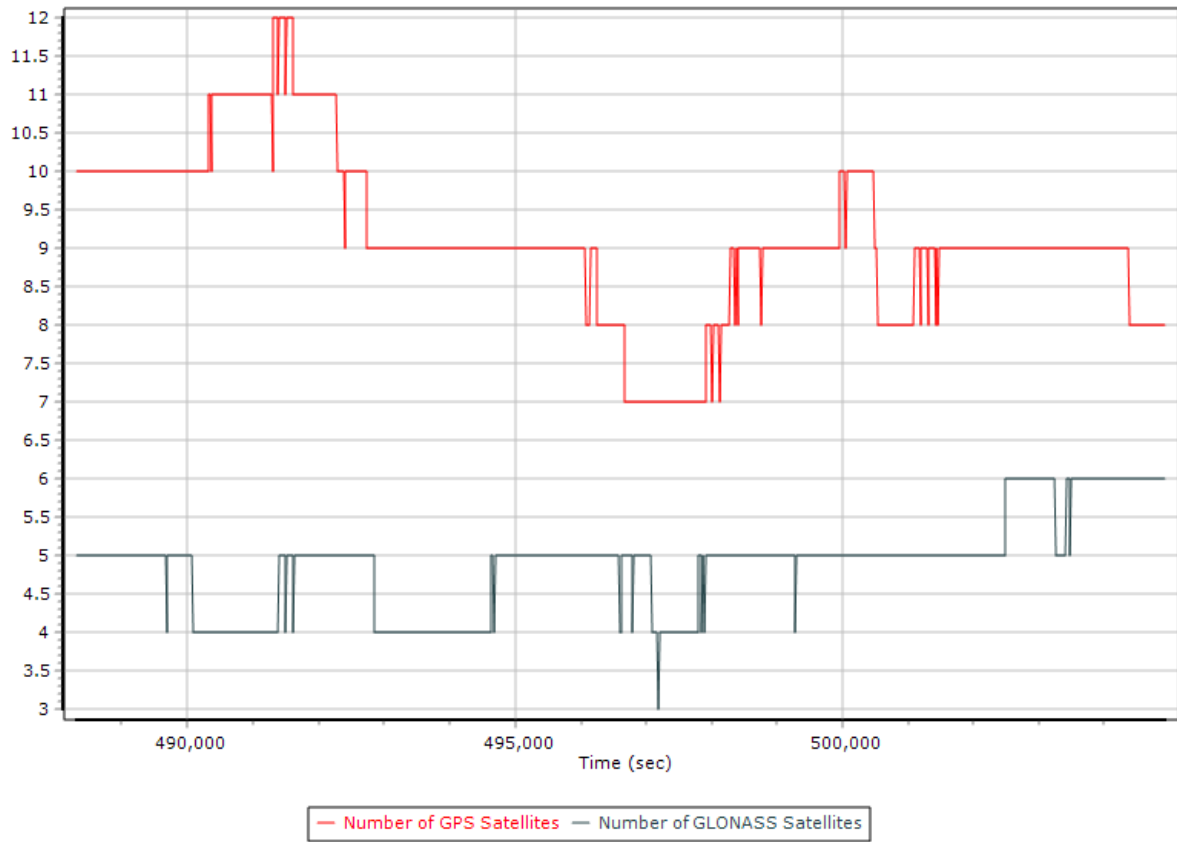
Y:

Z:

OK Cancel









Project Settings [X]

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

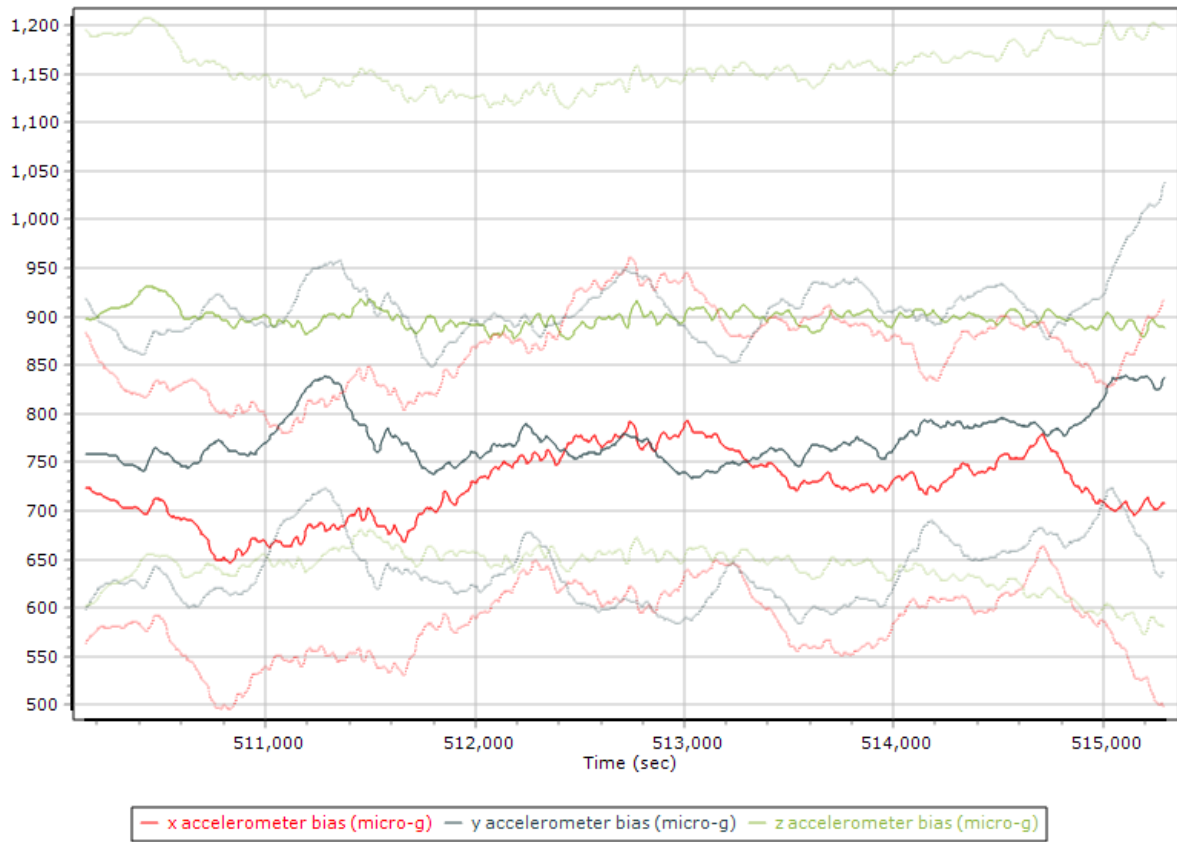
Timing

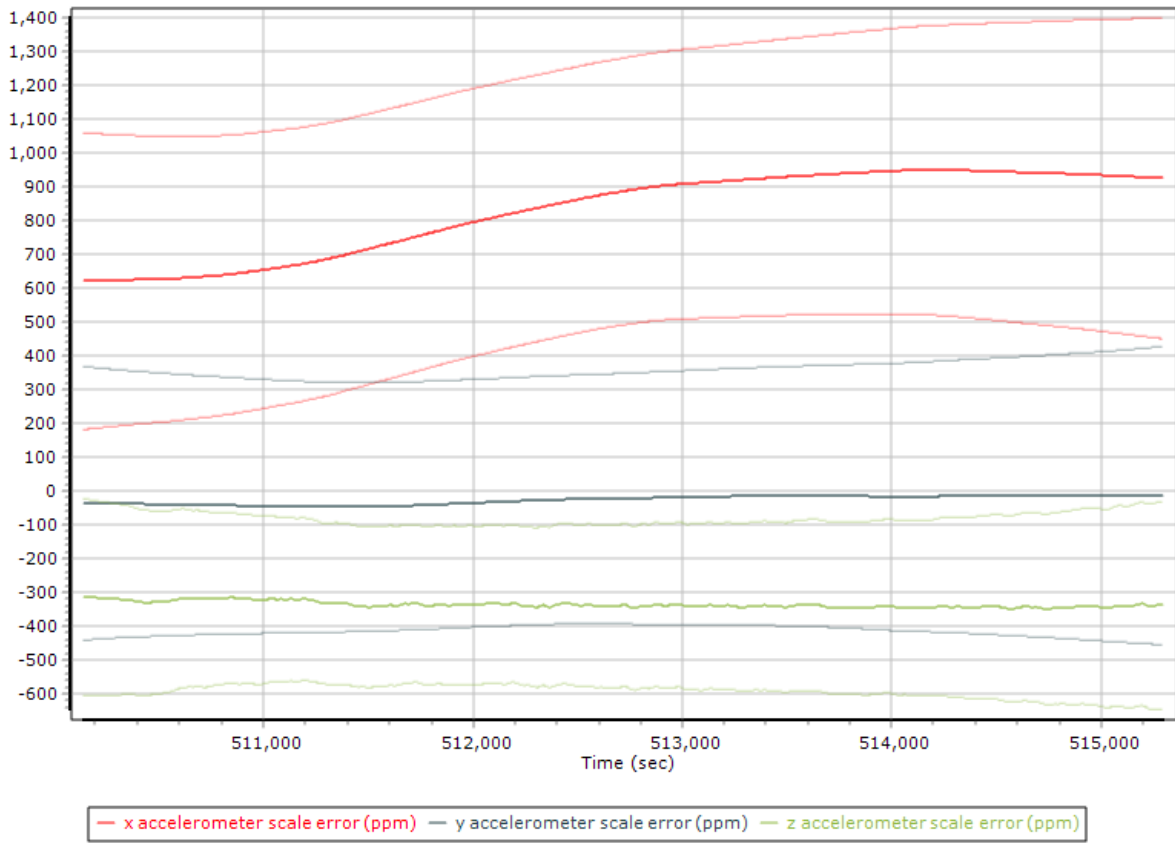
Start: 488297.153
 End: 504951.000
 Entire time interval
 Seconds of start week
 UTC Offset: 18.000

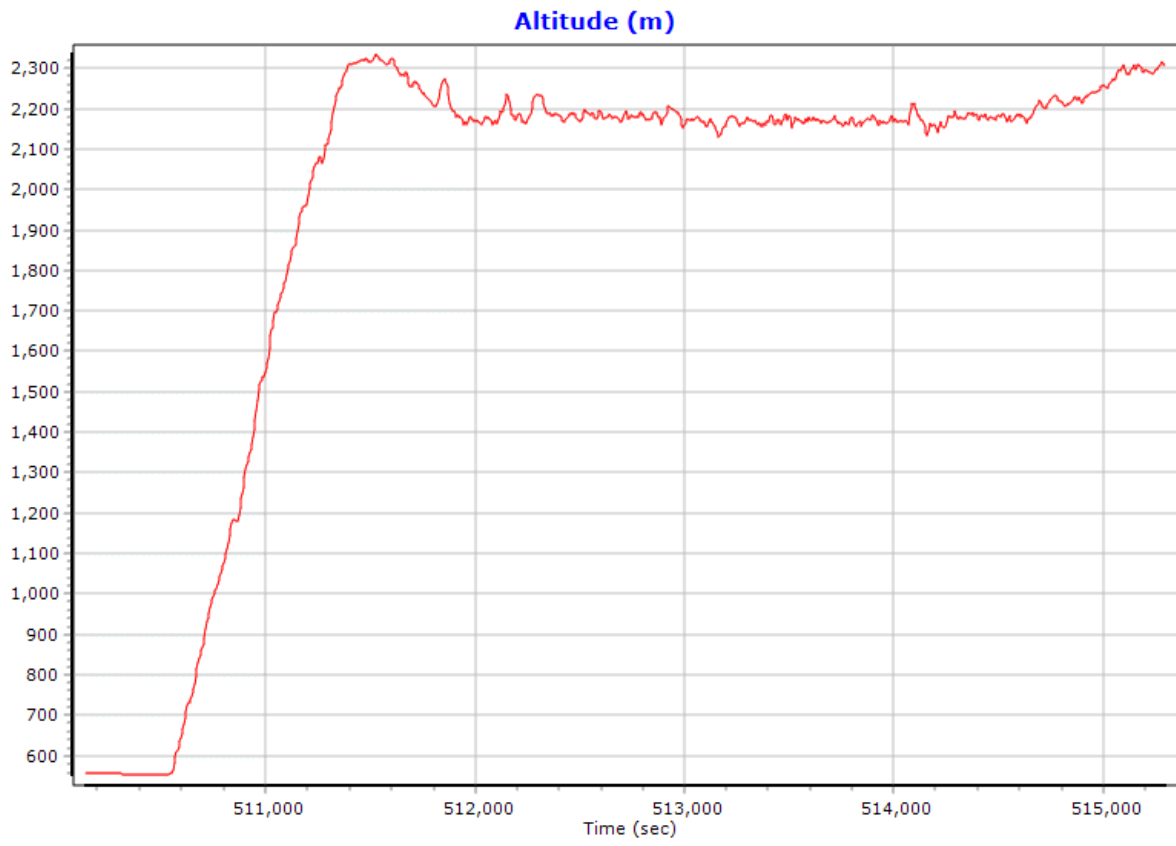
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel

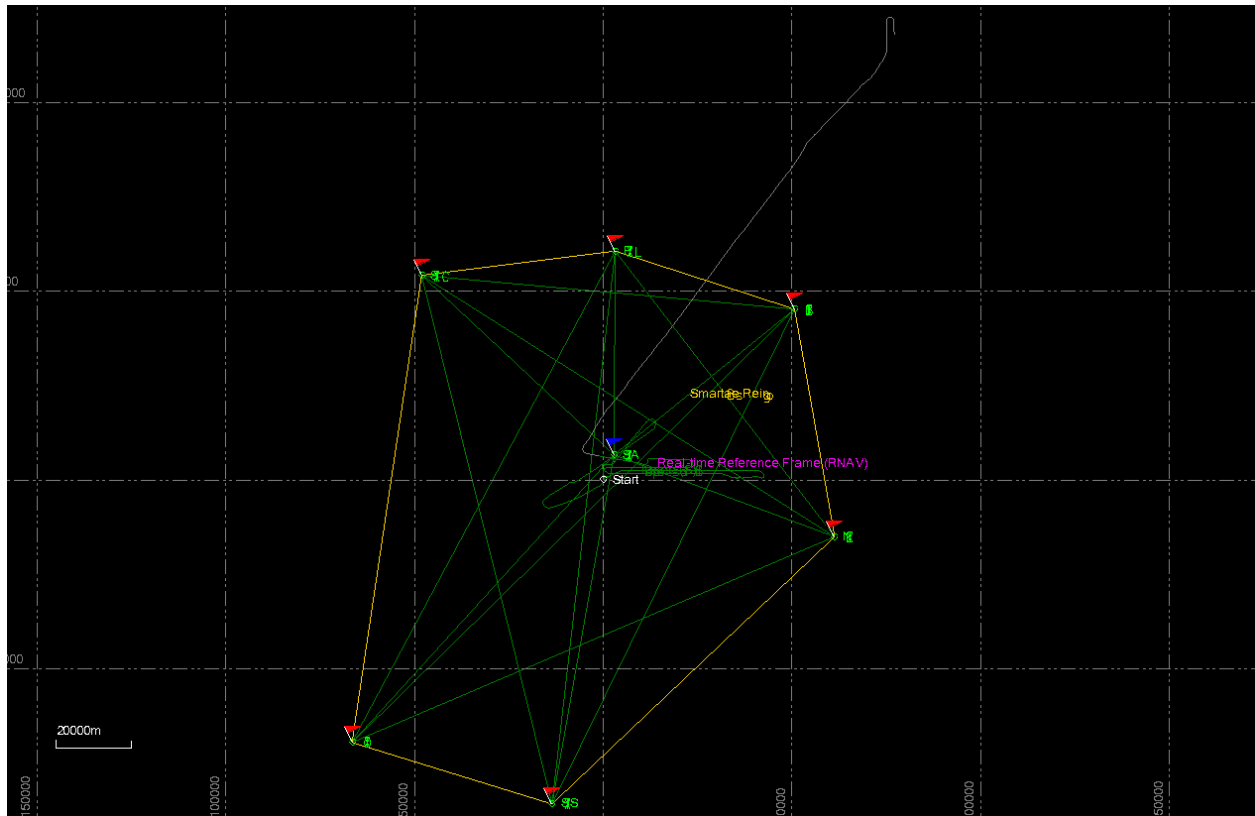
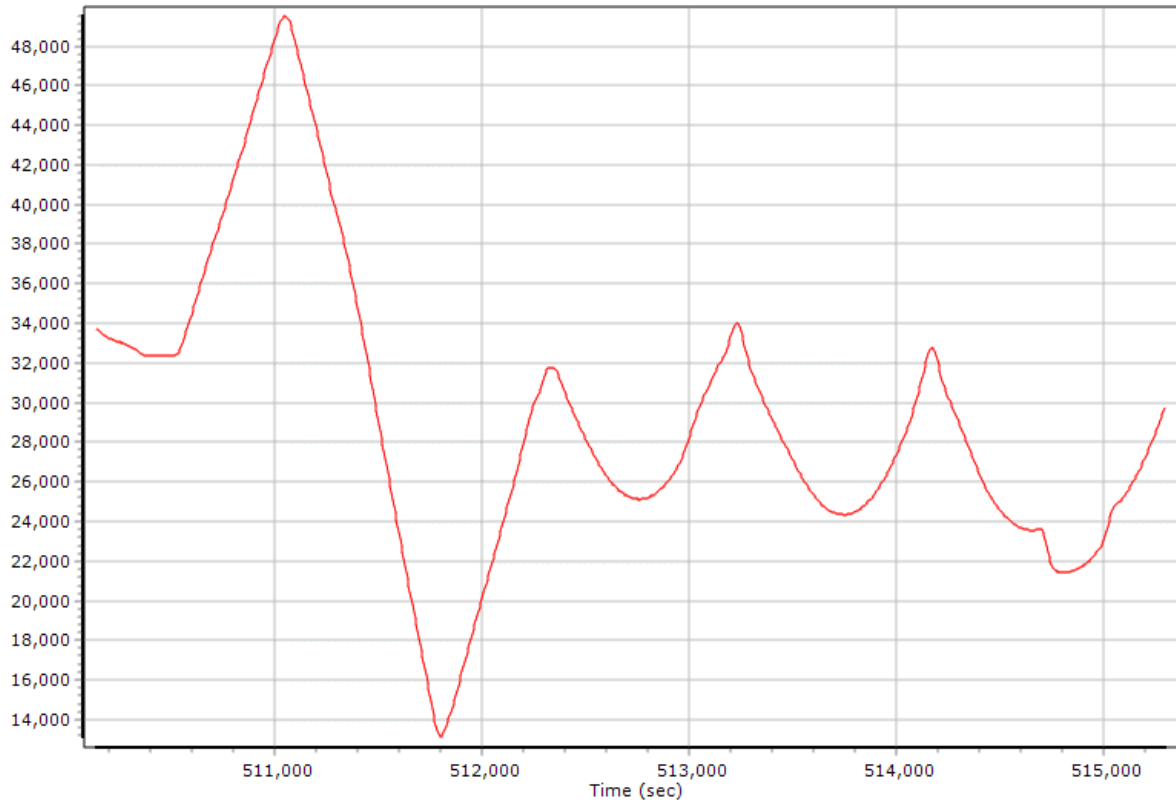
UNB18061B

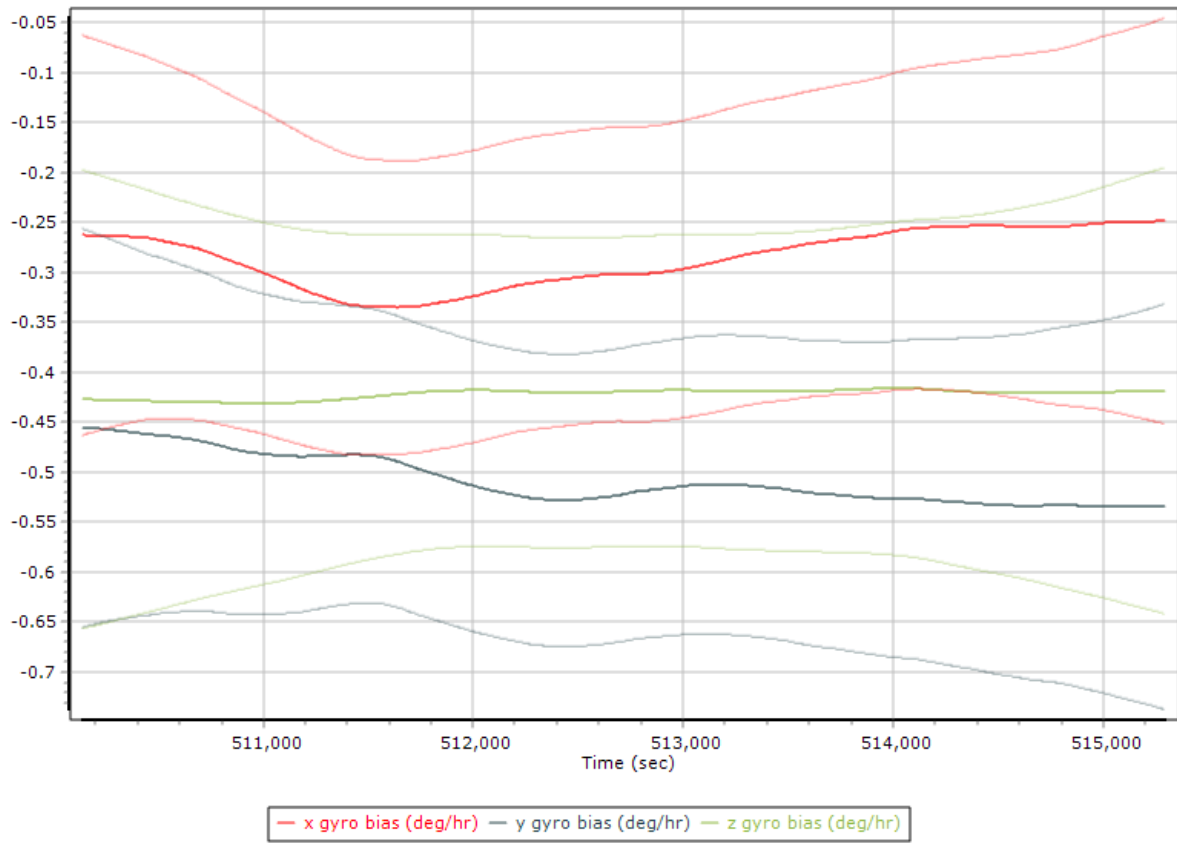


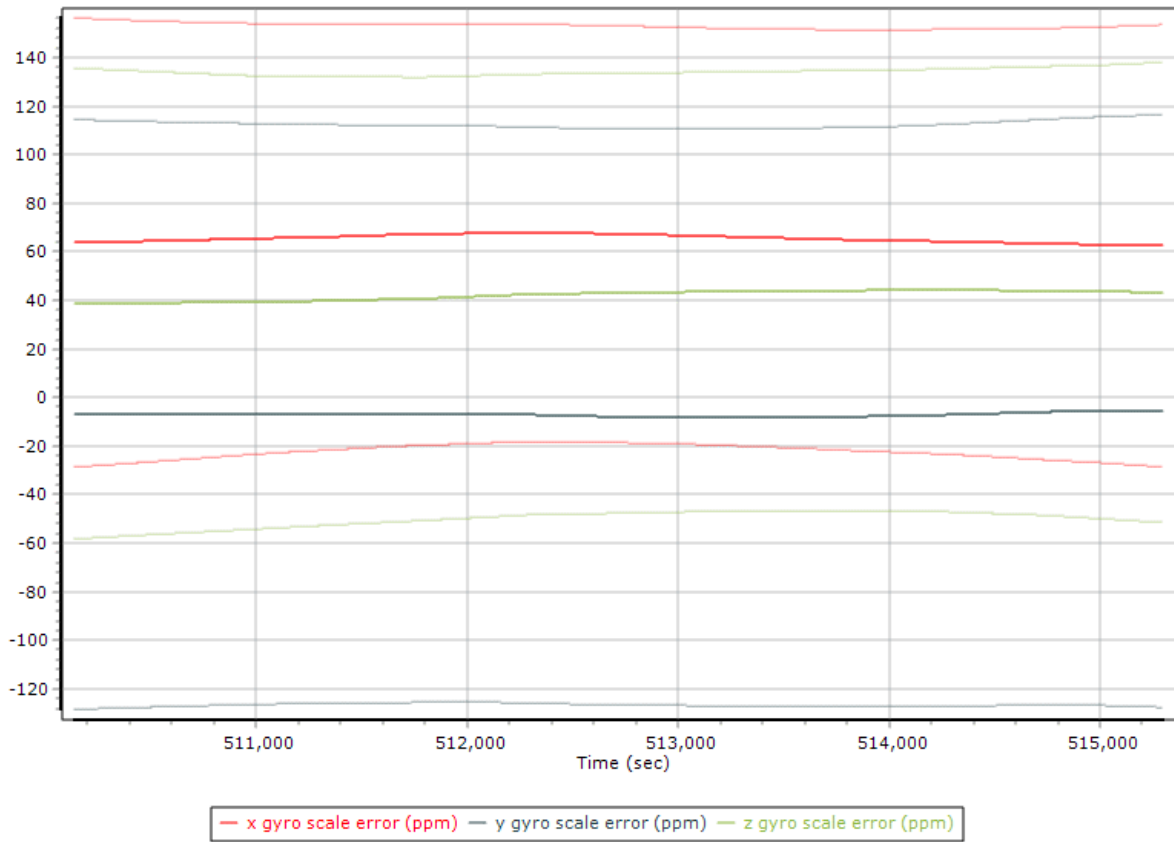




Baseline Length (m)







Project Settings [X]

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation: (Selected)

<3cm 10cm 50cm 1m 10m

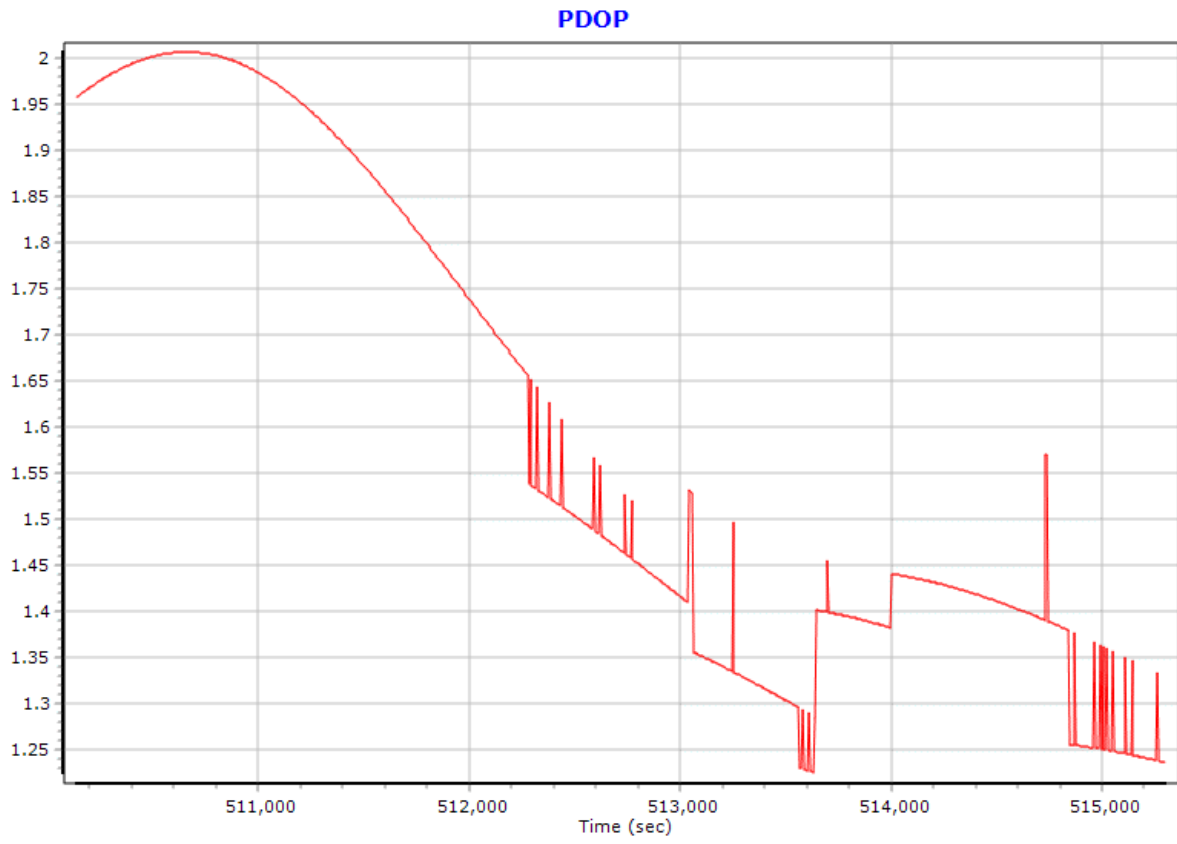
Aircraft to Reference Mounting Angles

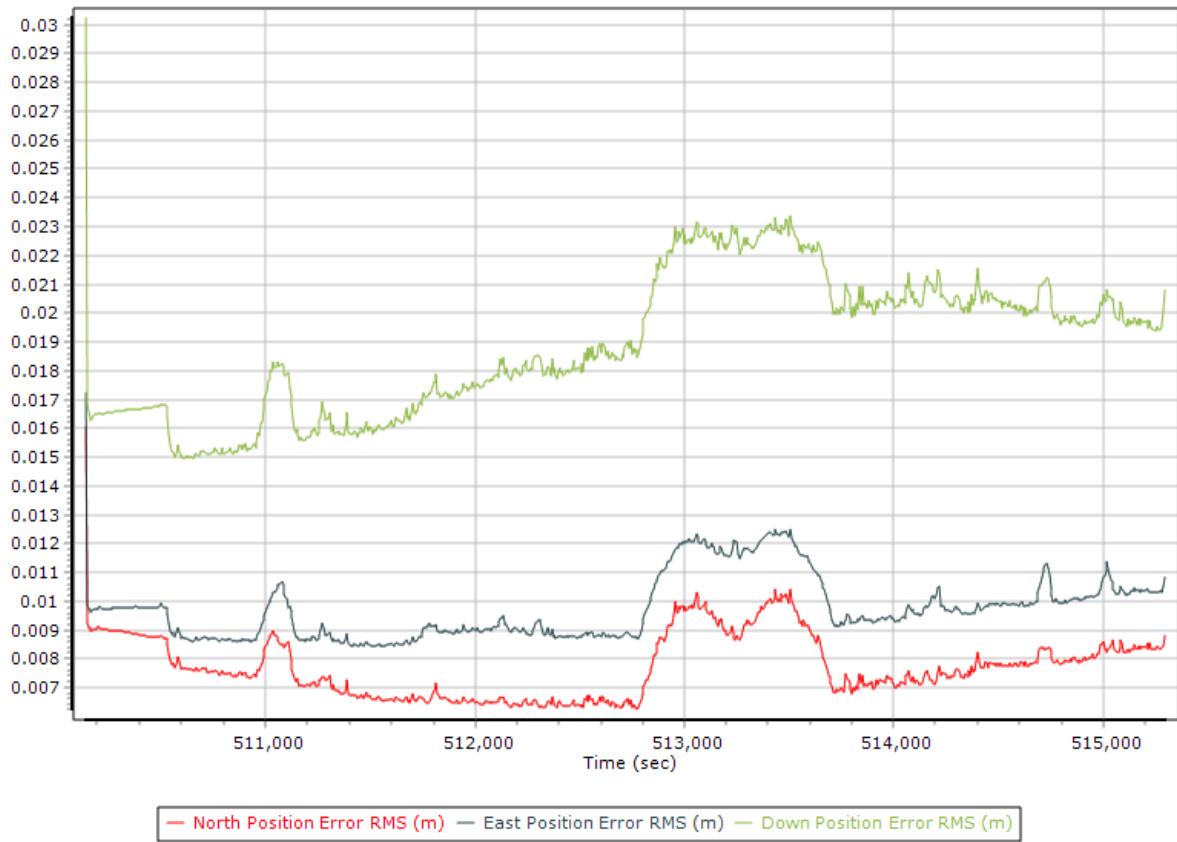
X:

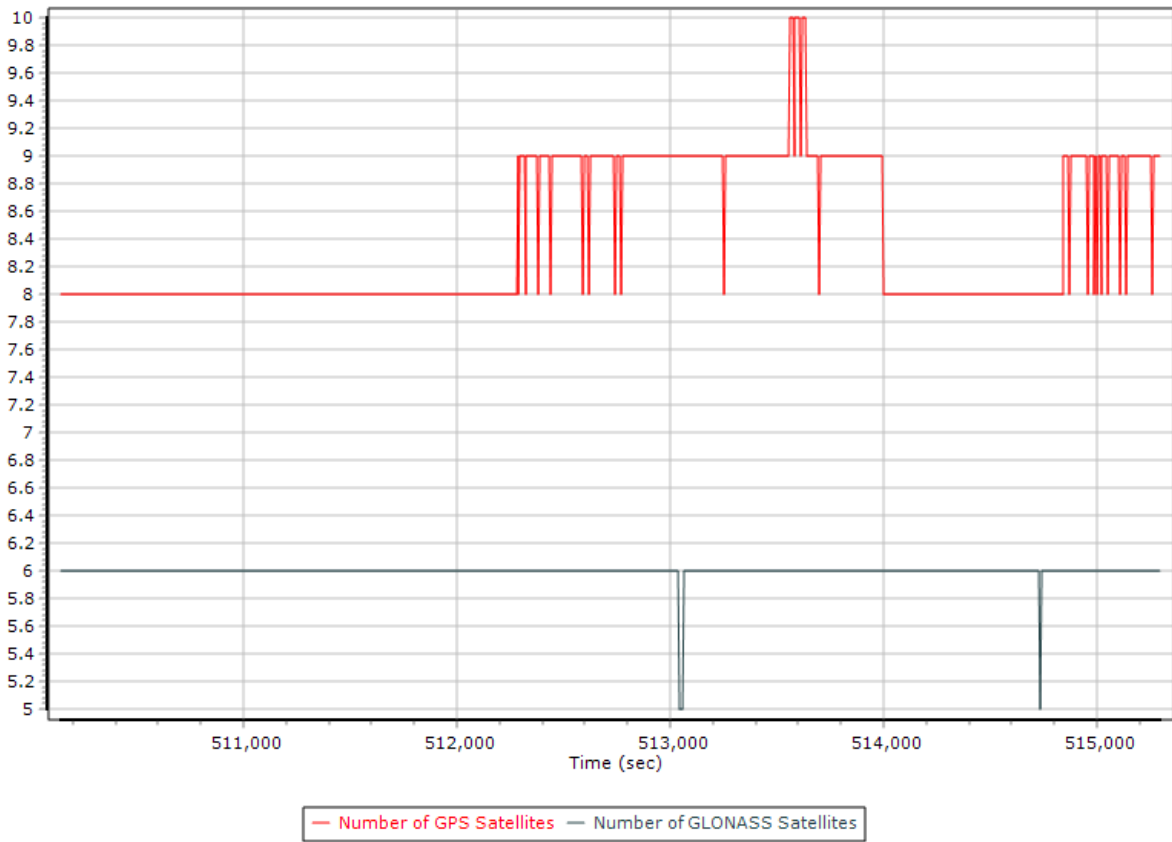
Y:

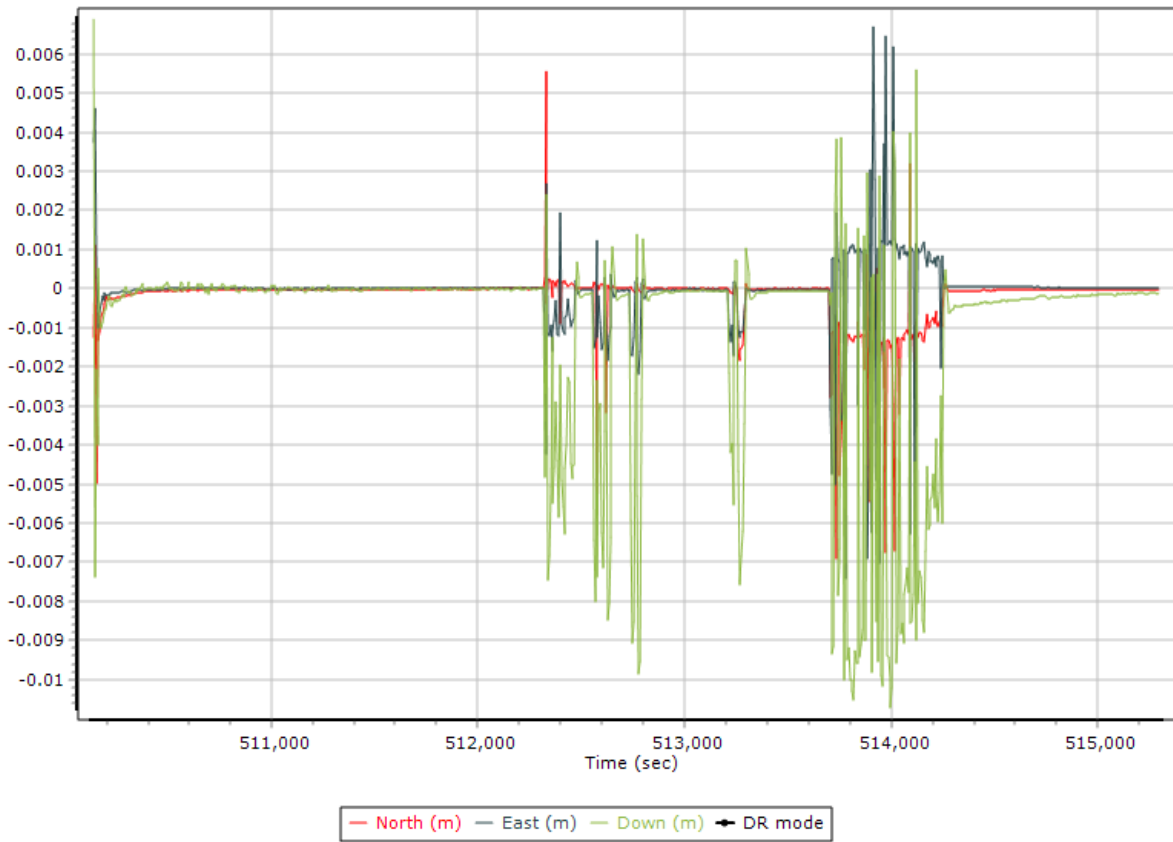
Z:

OK Cancel









Project Settings [X]

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

Timing

Start: 509538.000
 End: 515301.925

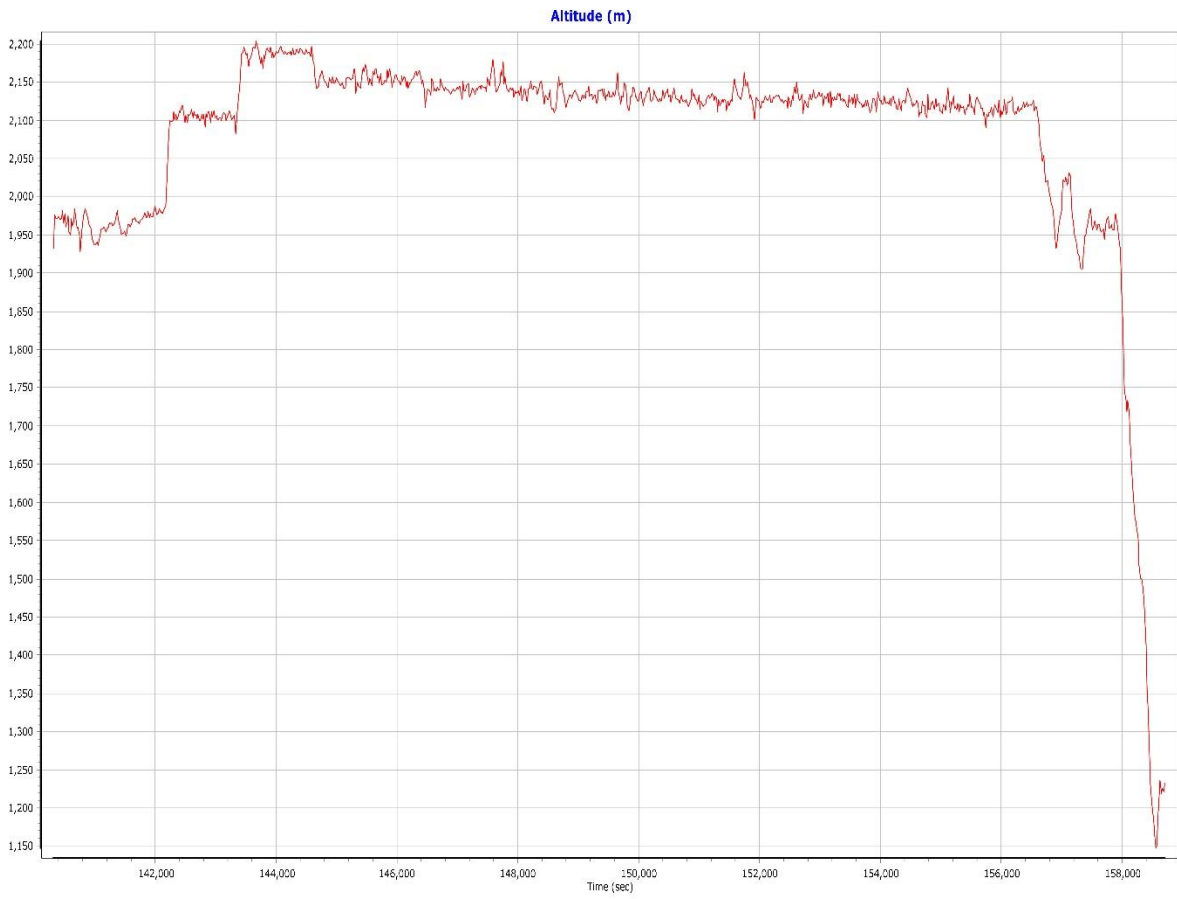
Entire time interval
 Seconds of start week

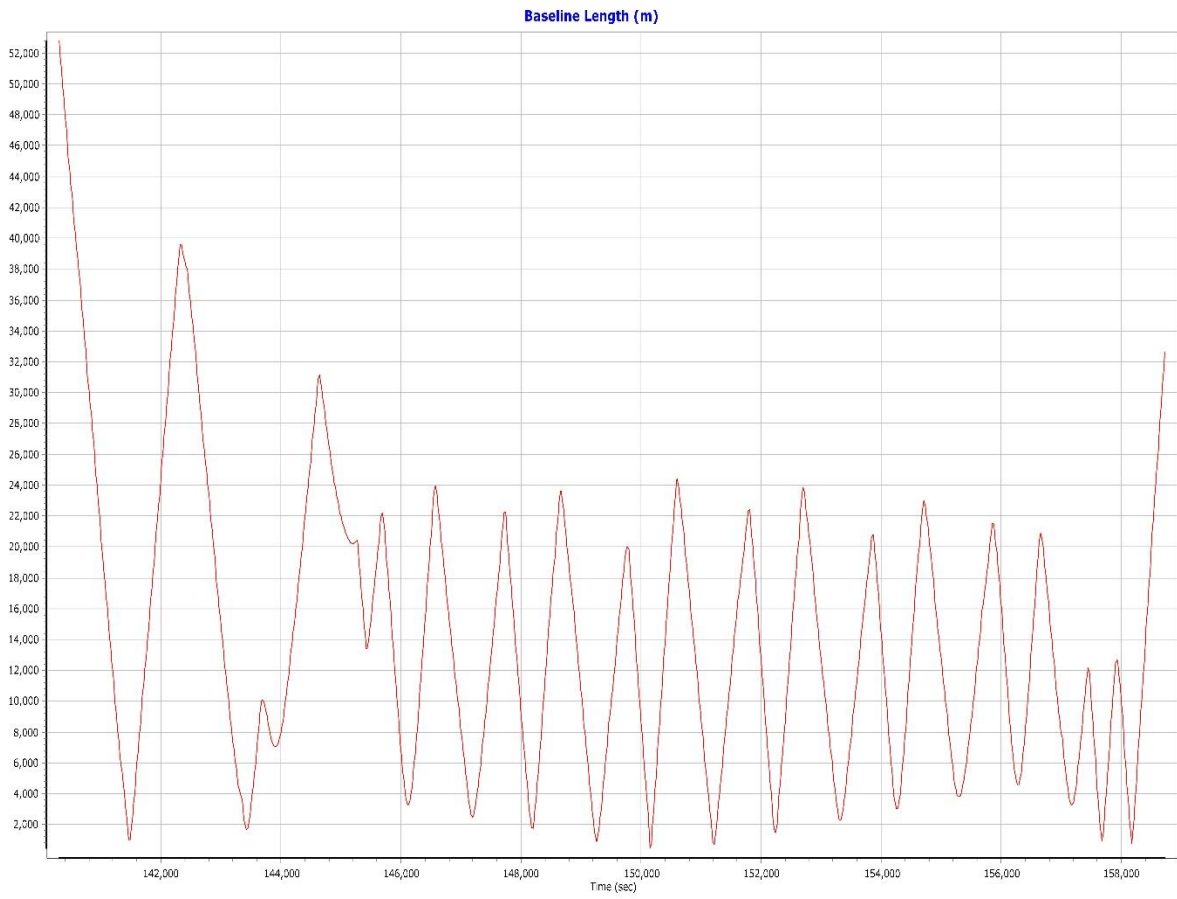
UTC Offset: 18.000

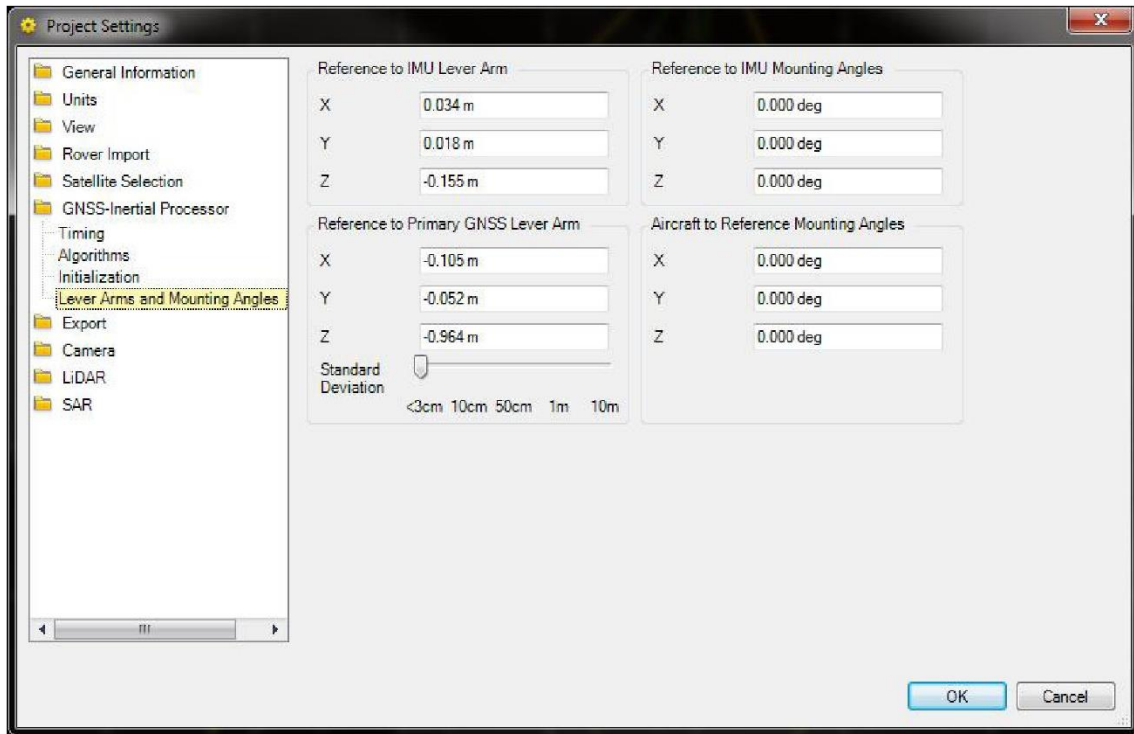
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

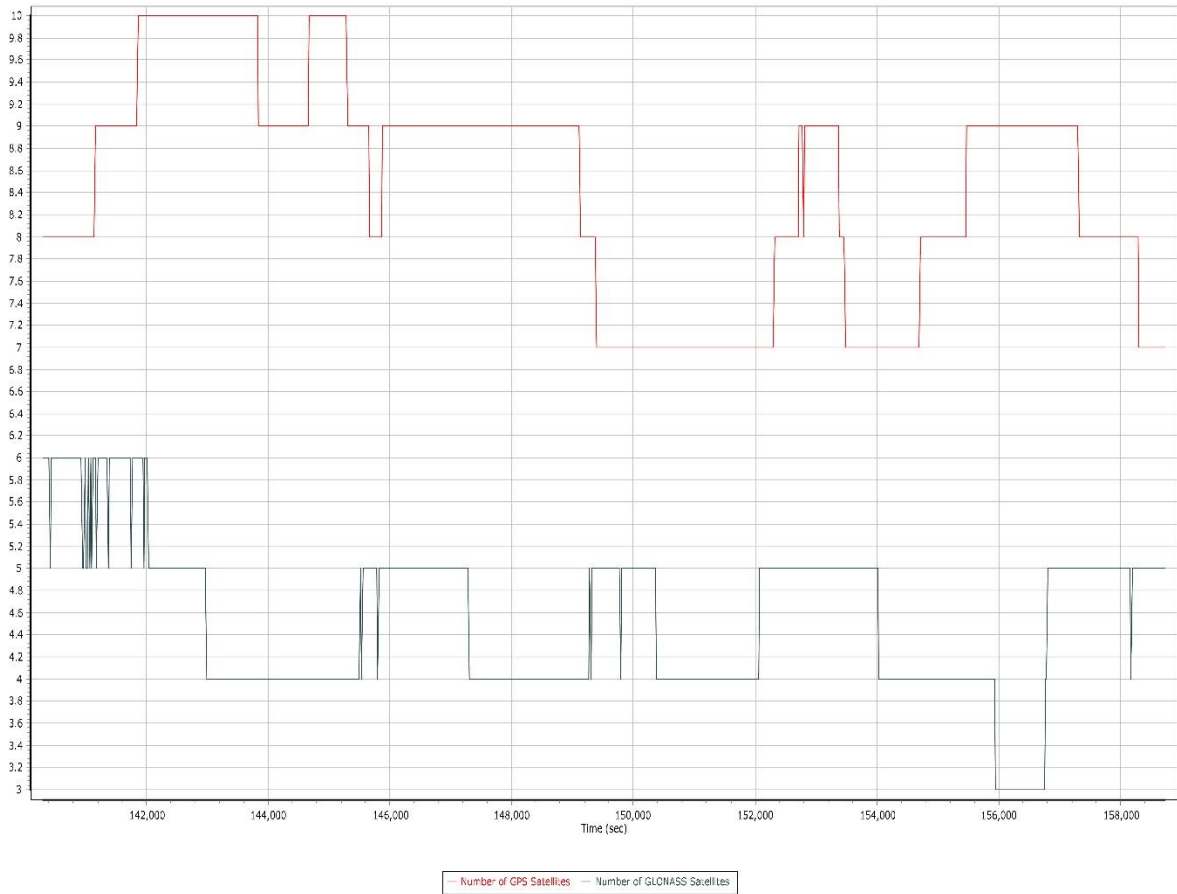
OK Cancel

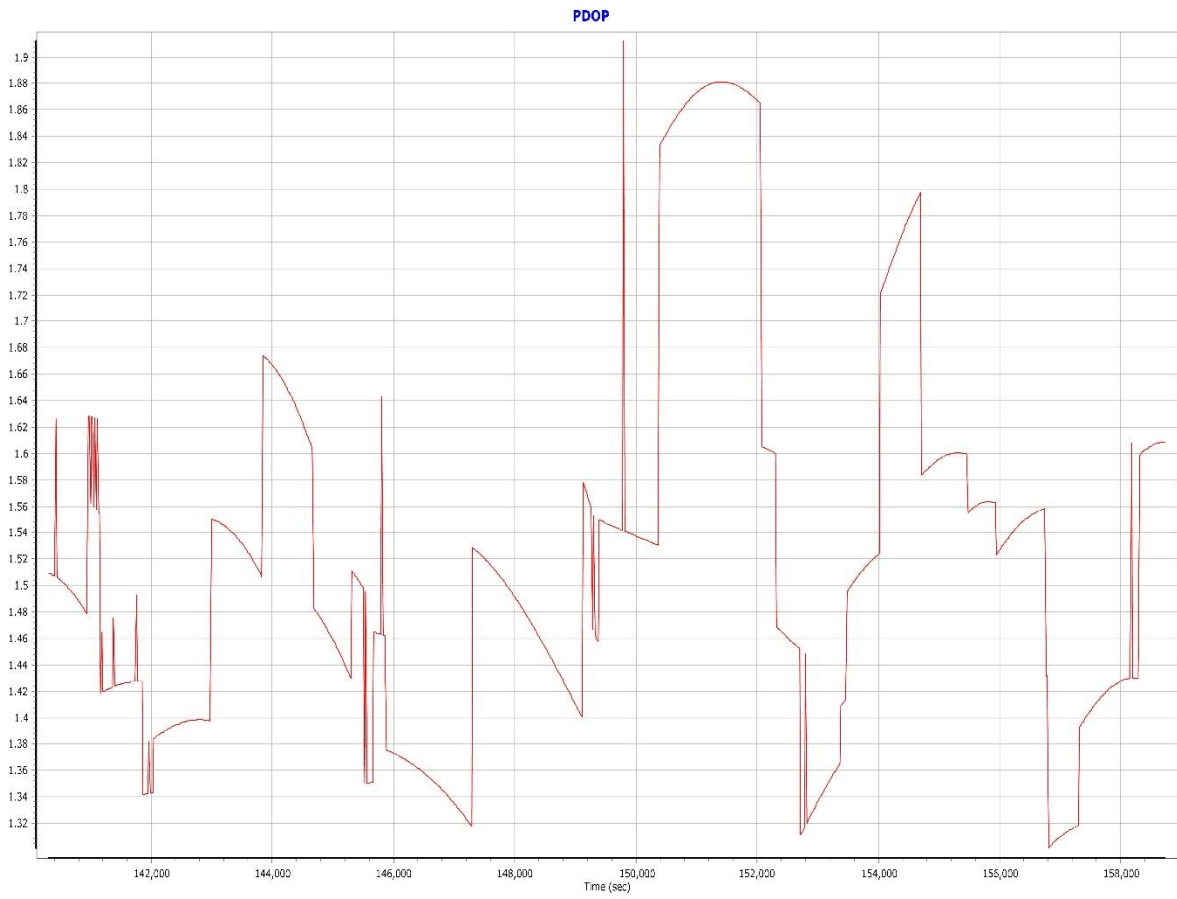
UNB18064A

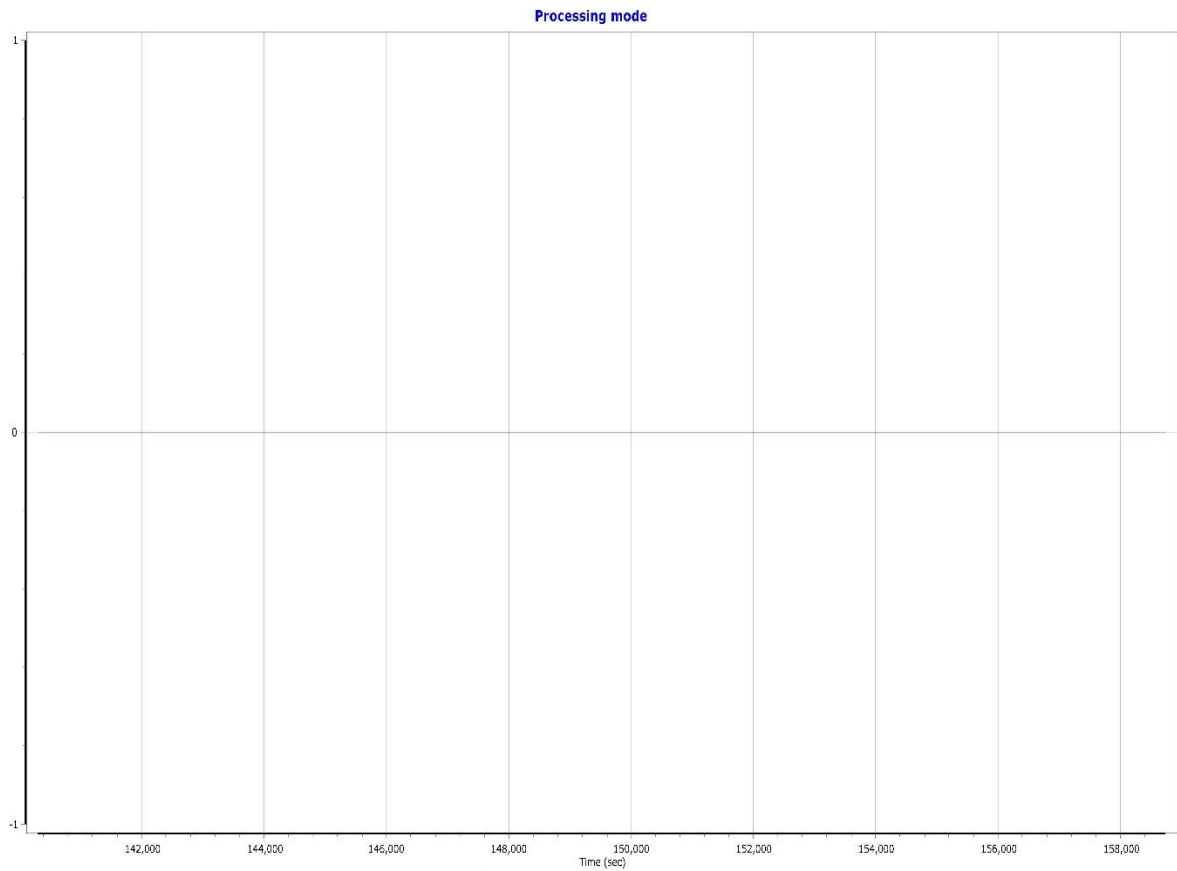




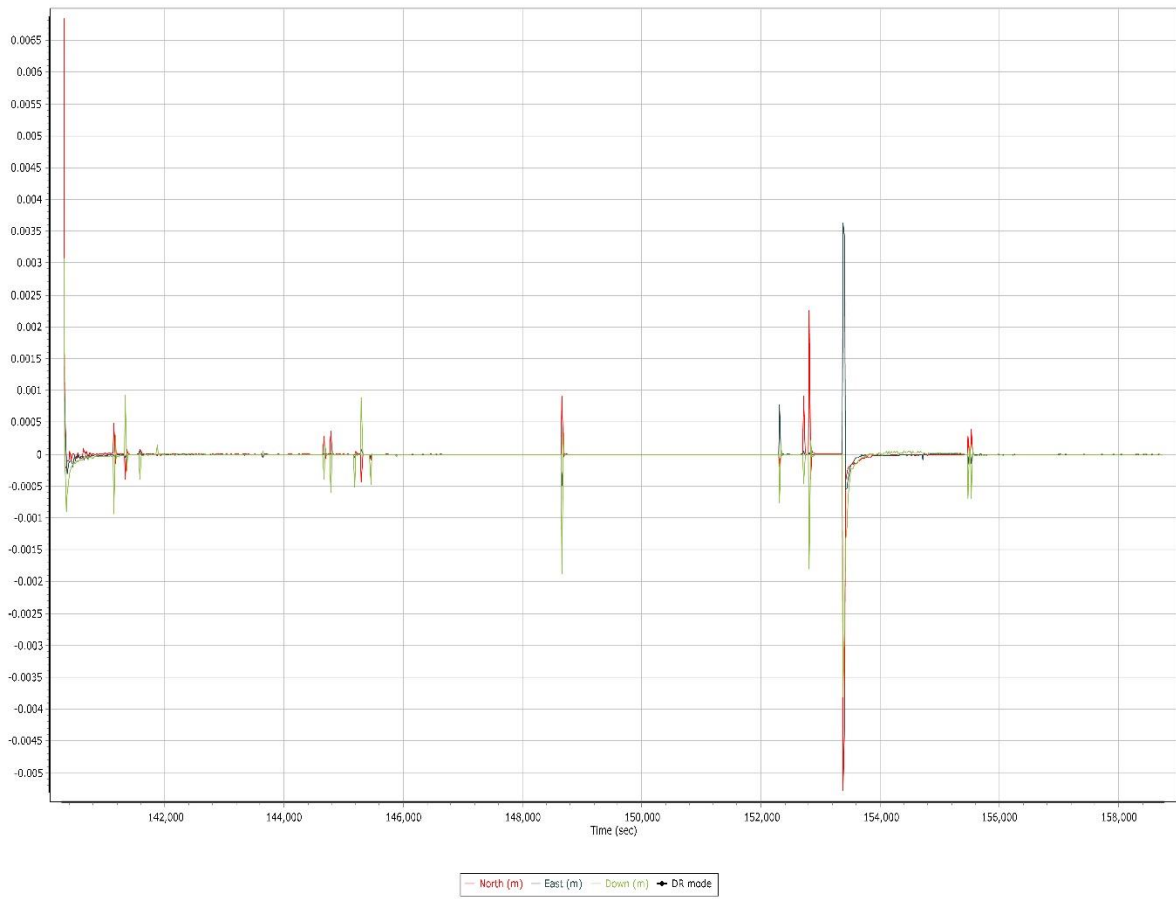


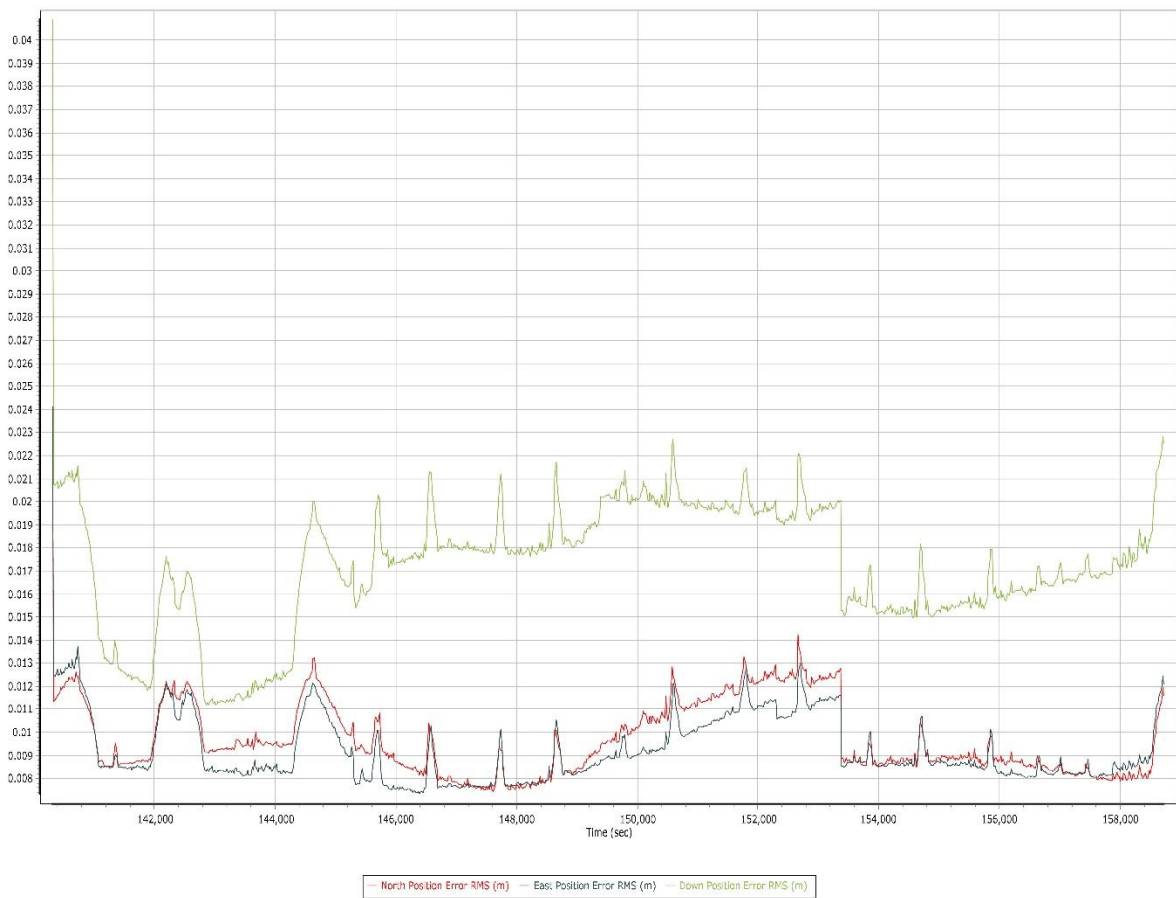


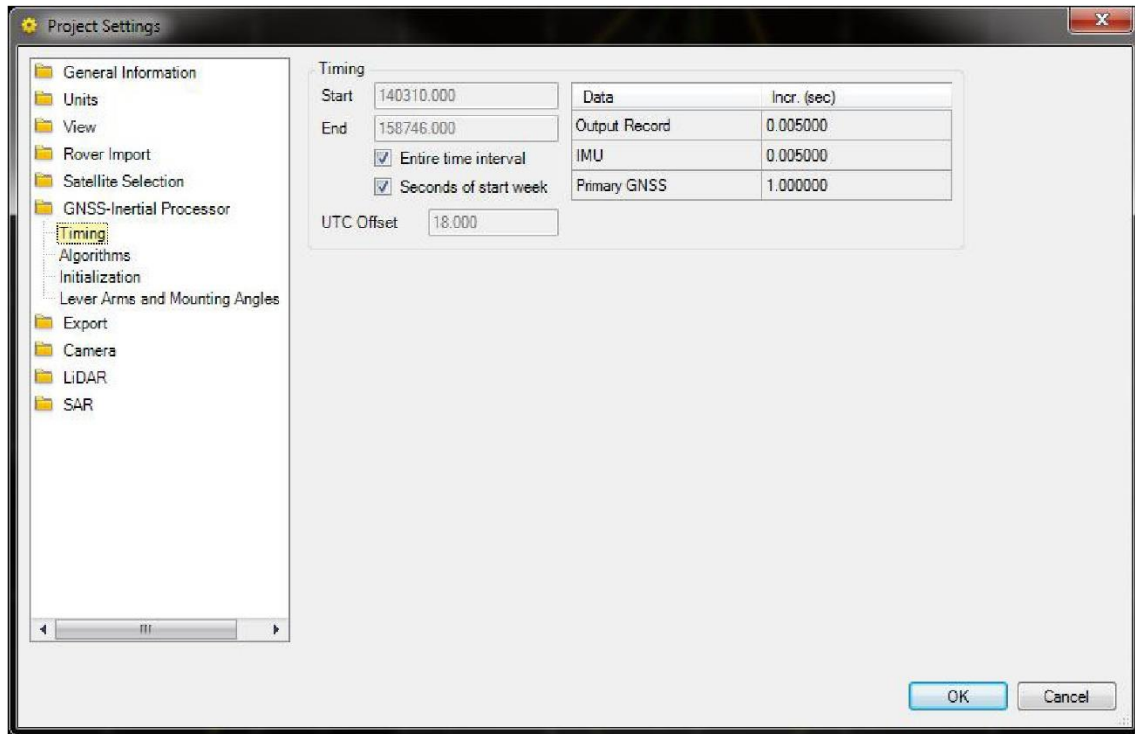


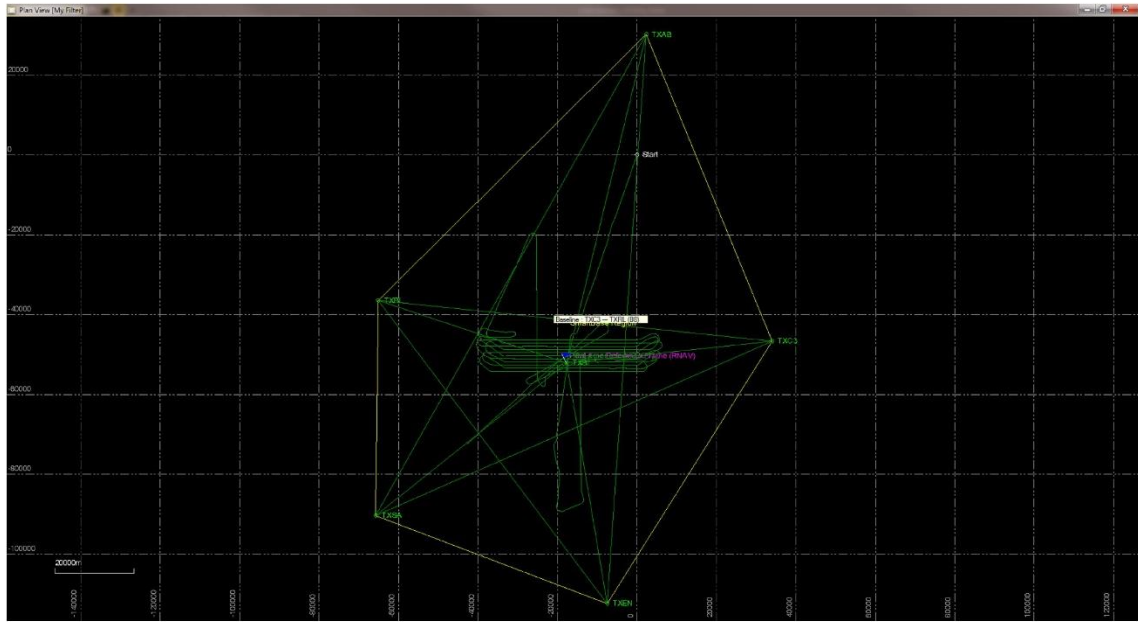


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IA*PPF, 6 = C/A, 7 = GNSS Nav, 8 = DR

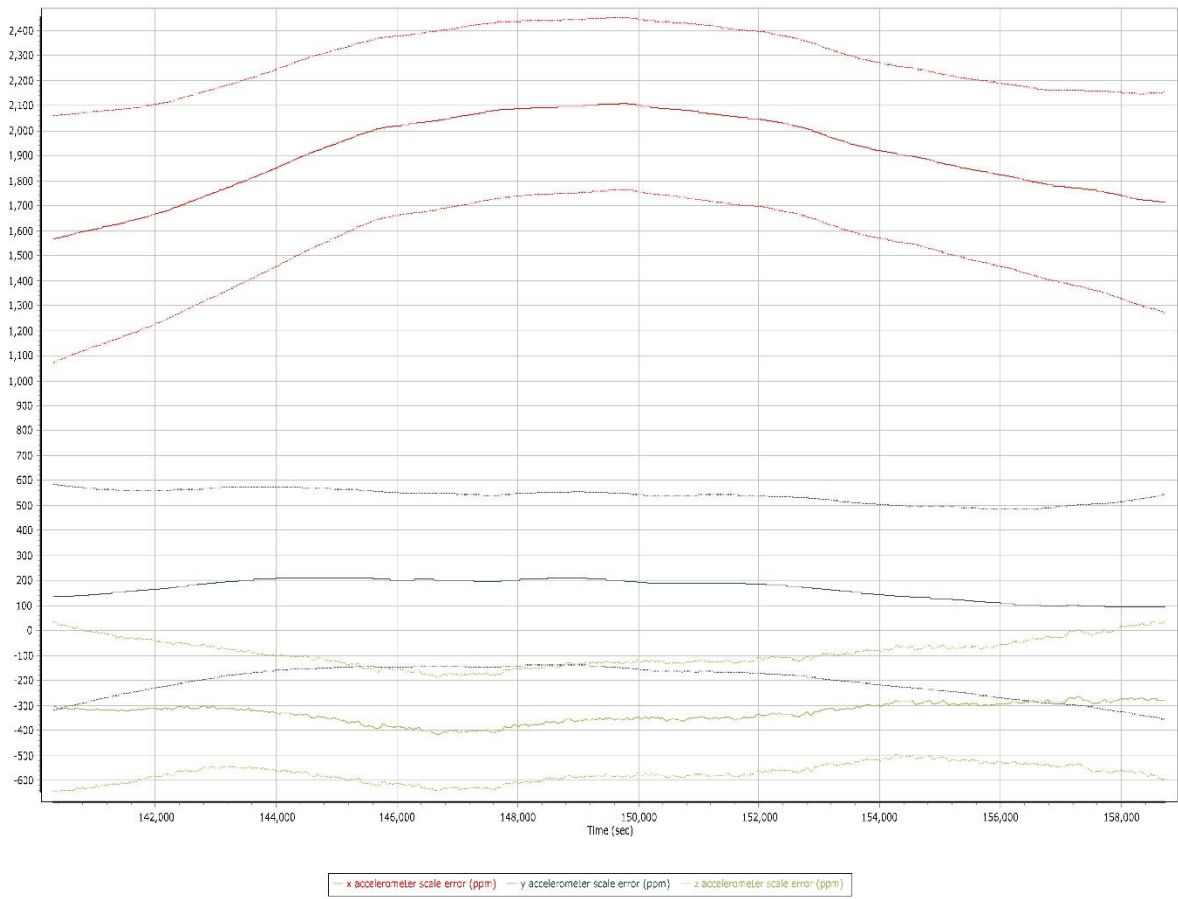


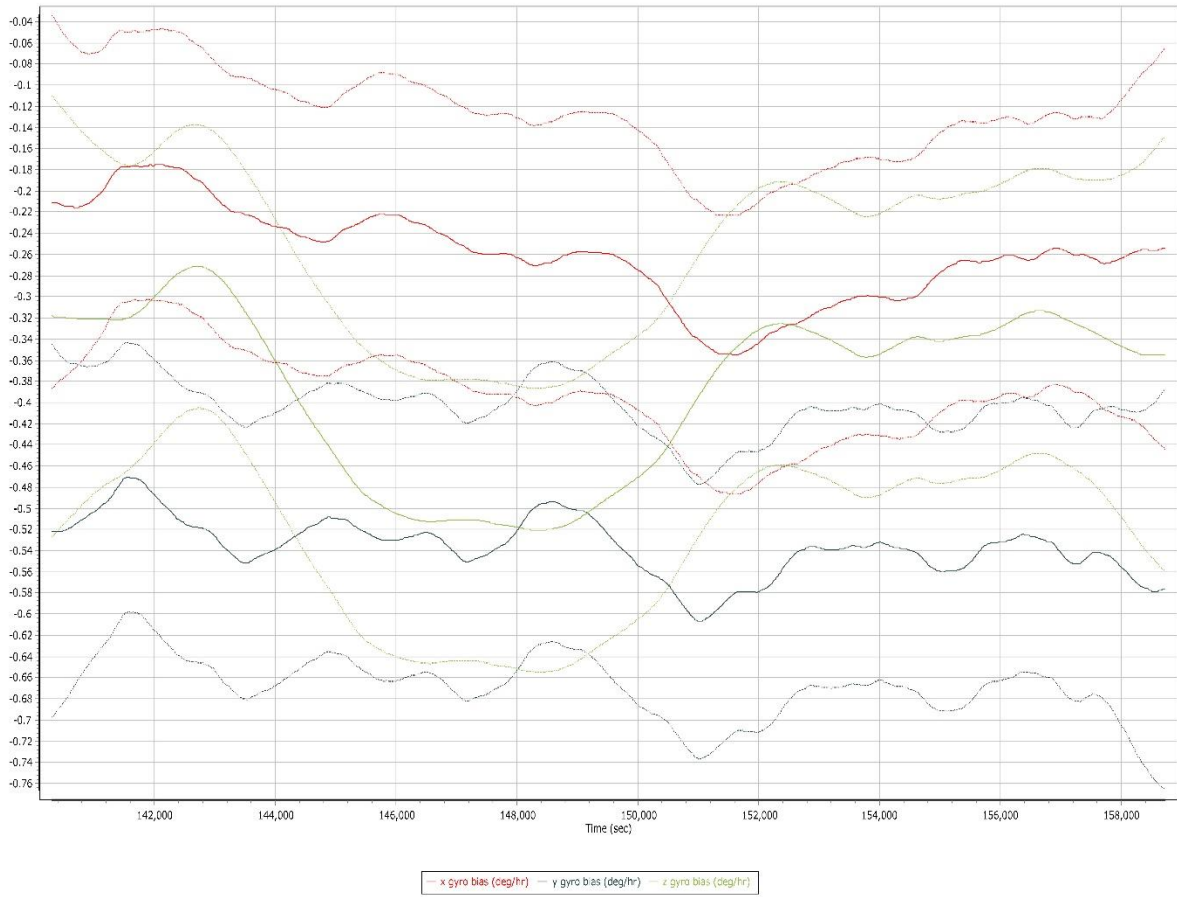


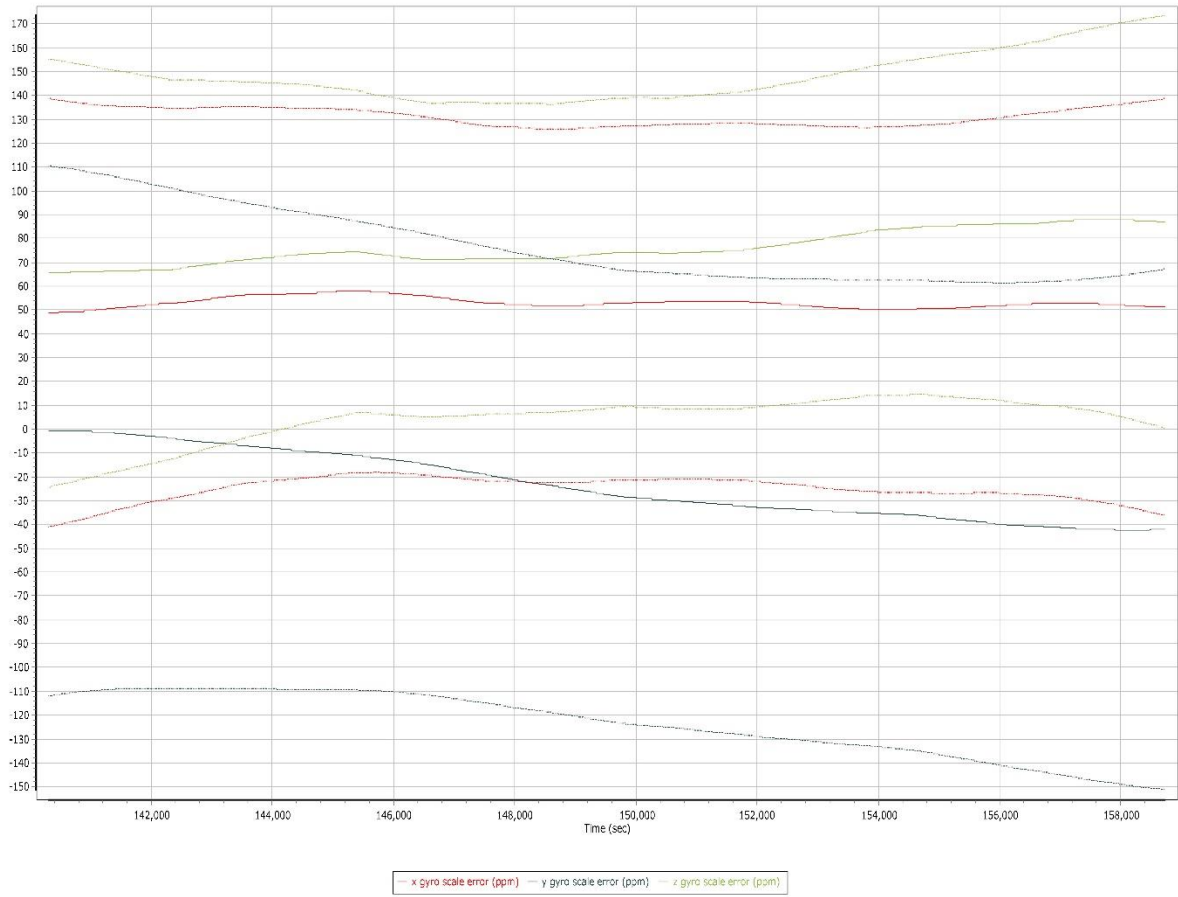




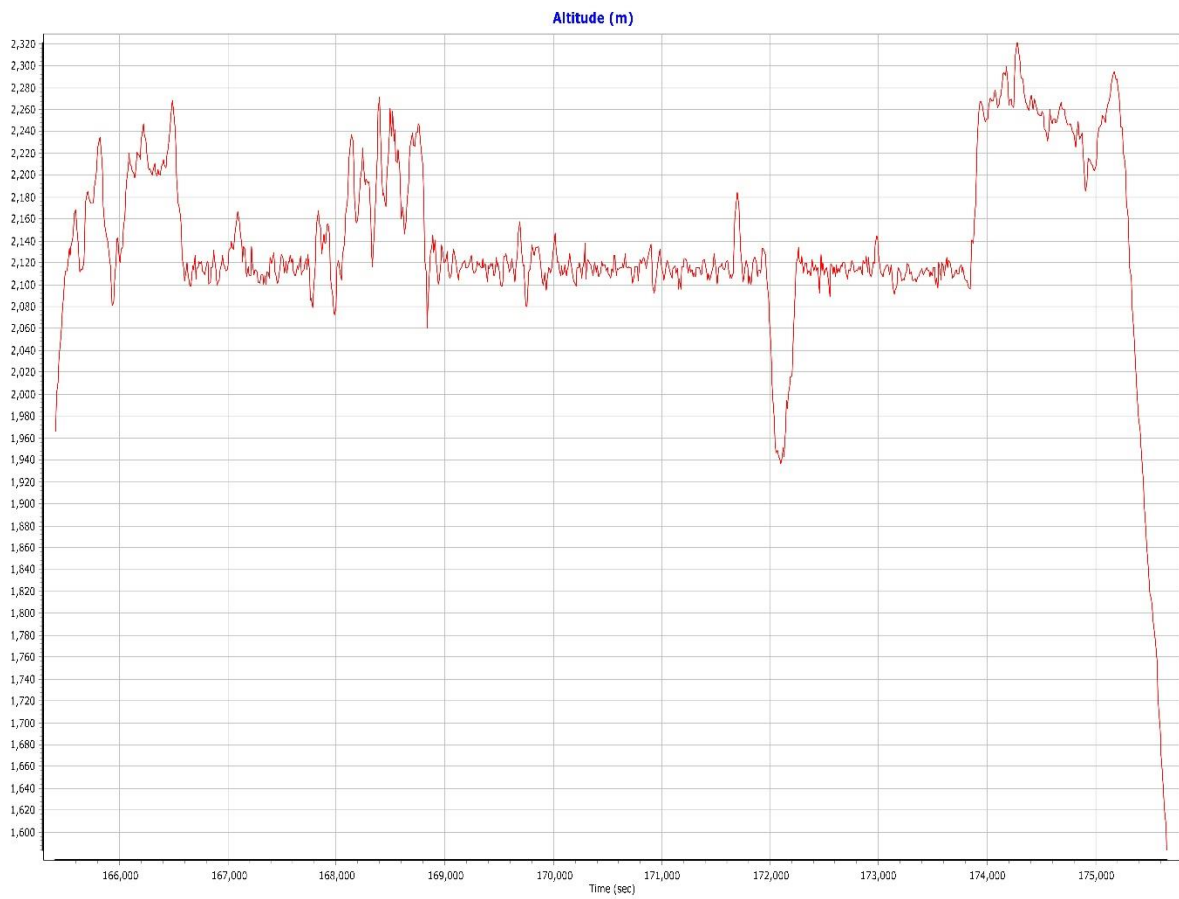


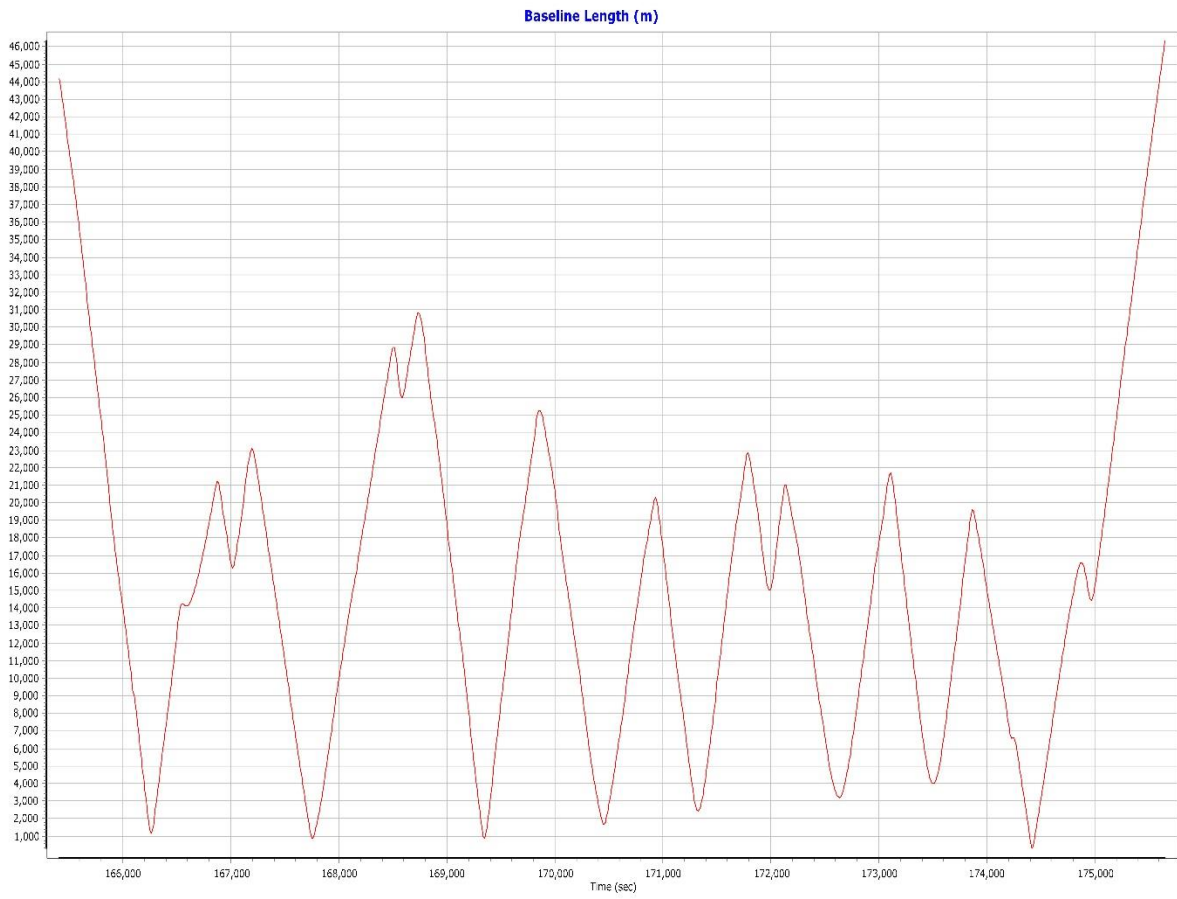


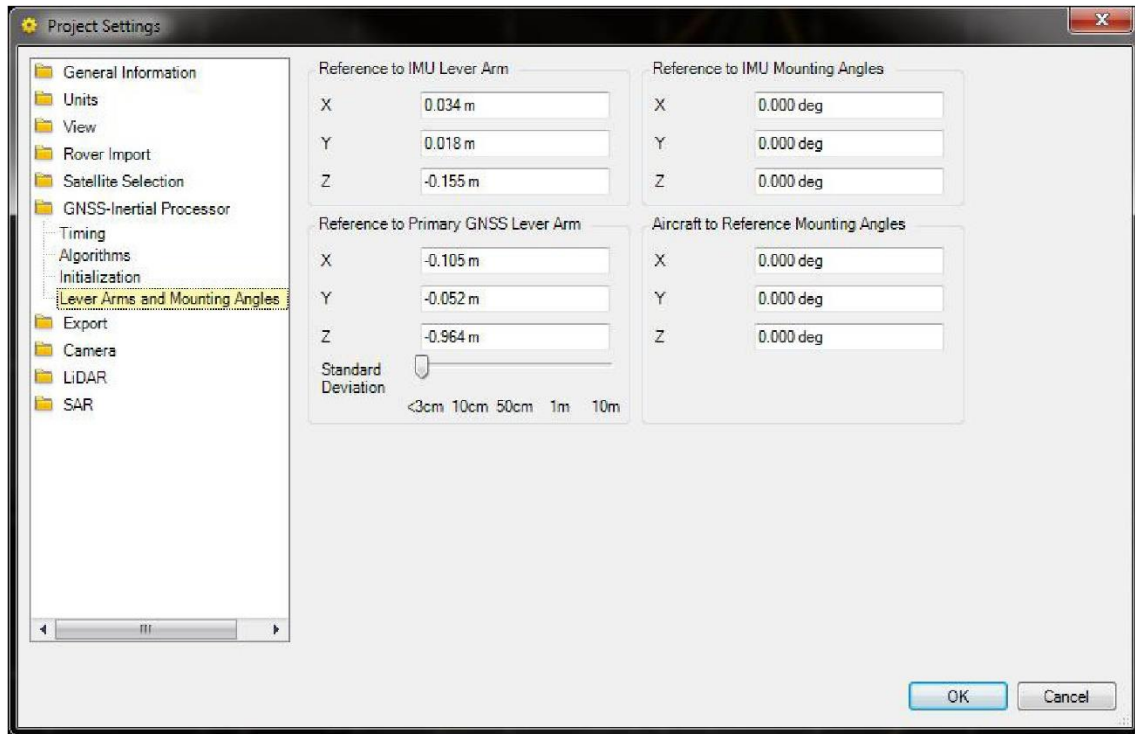


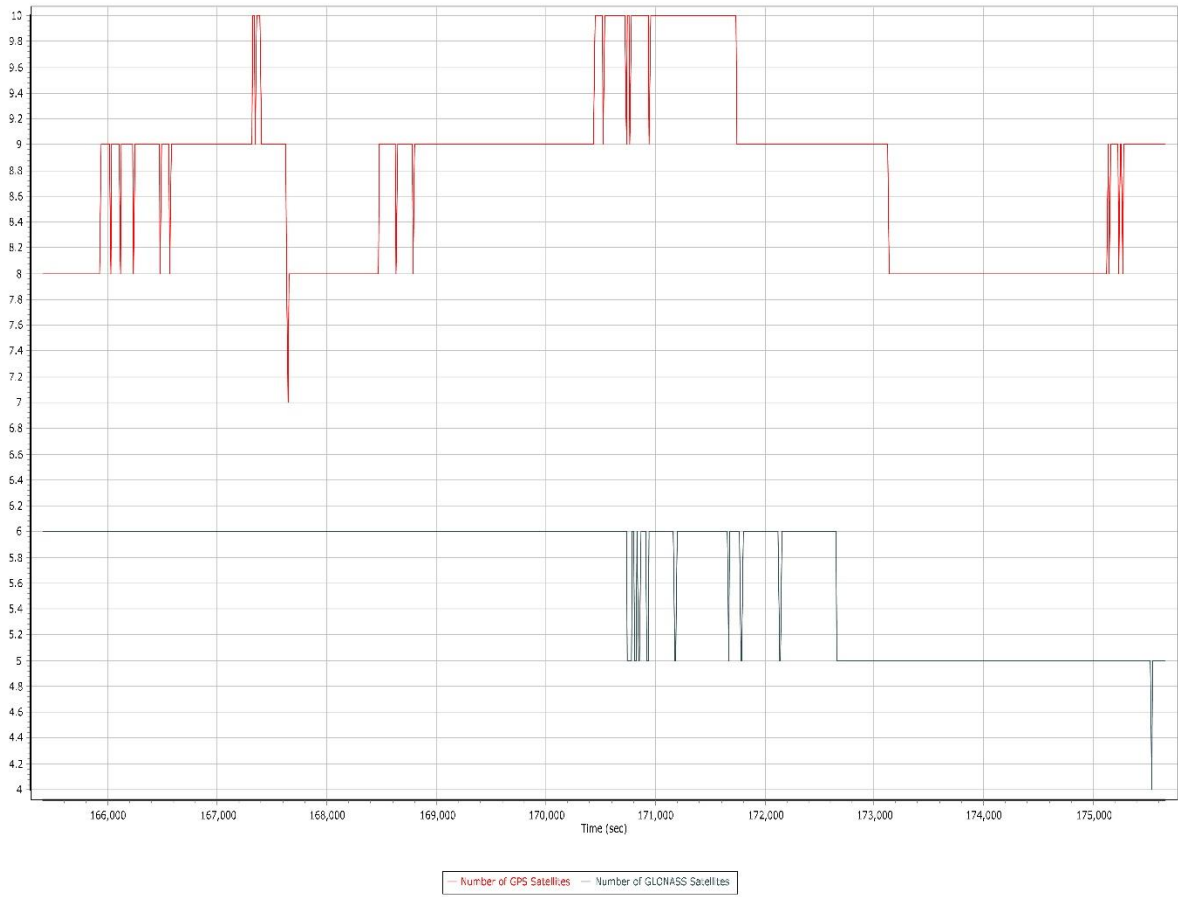


UNB18064B

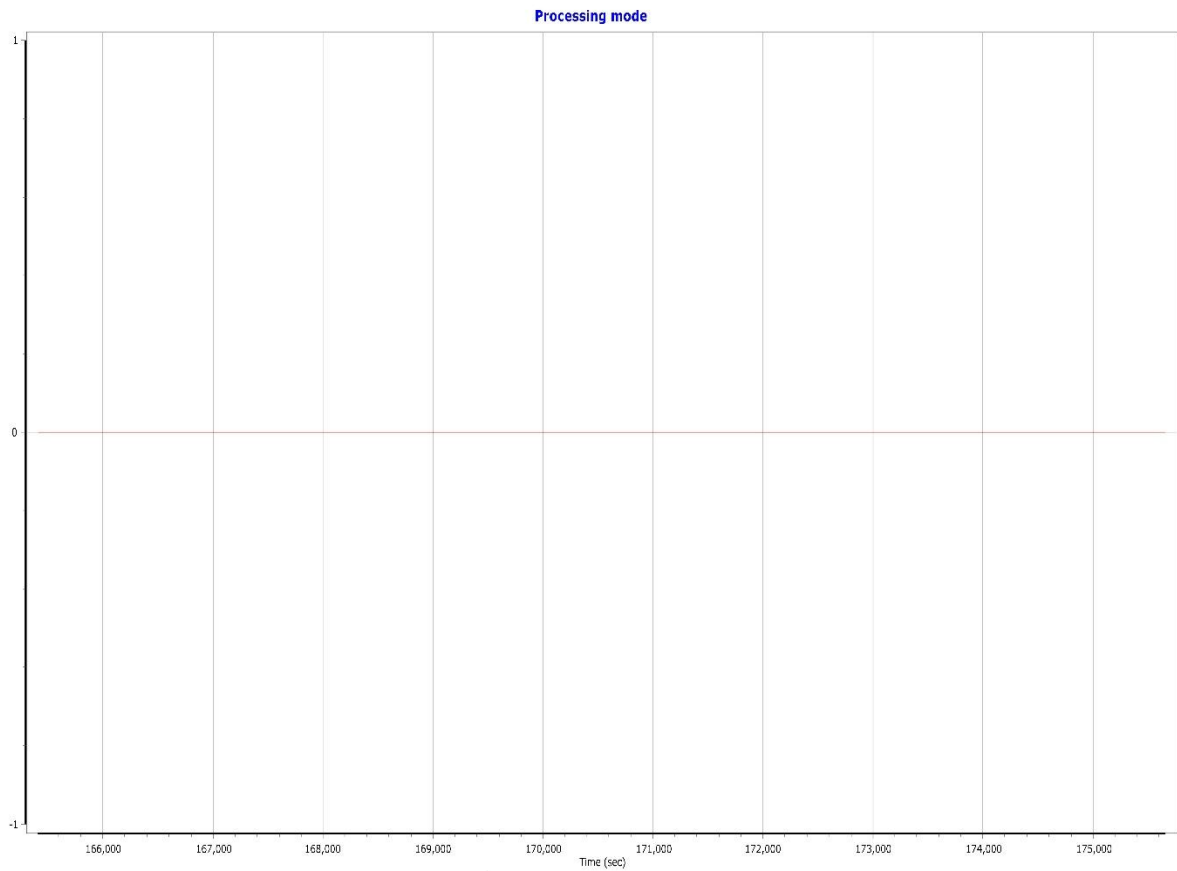




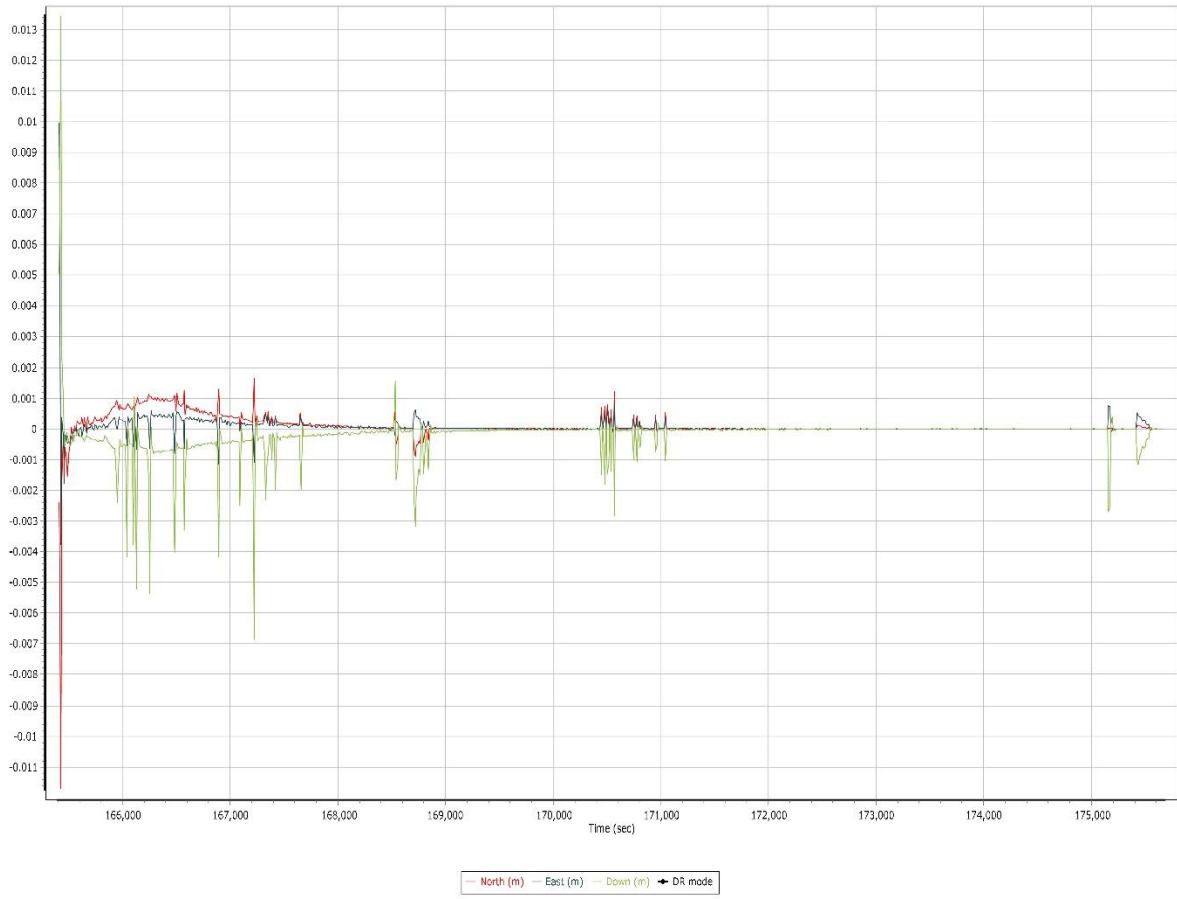


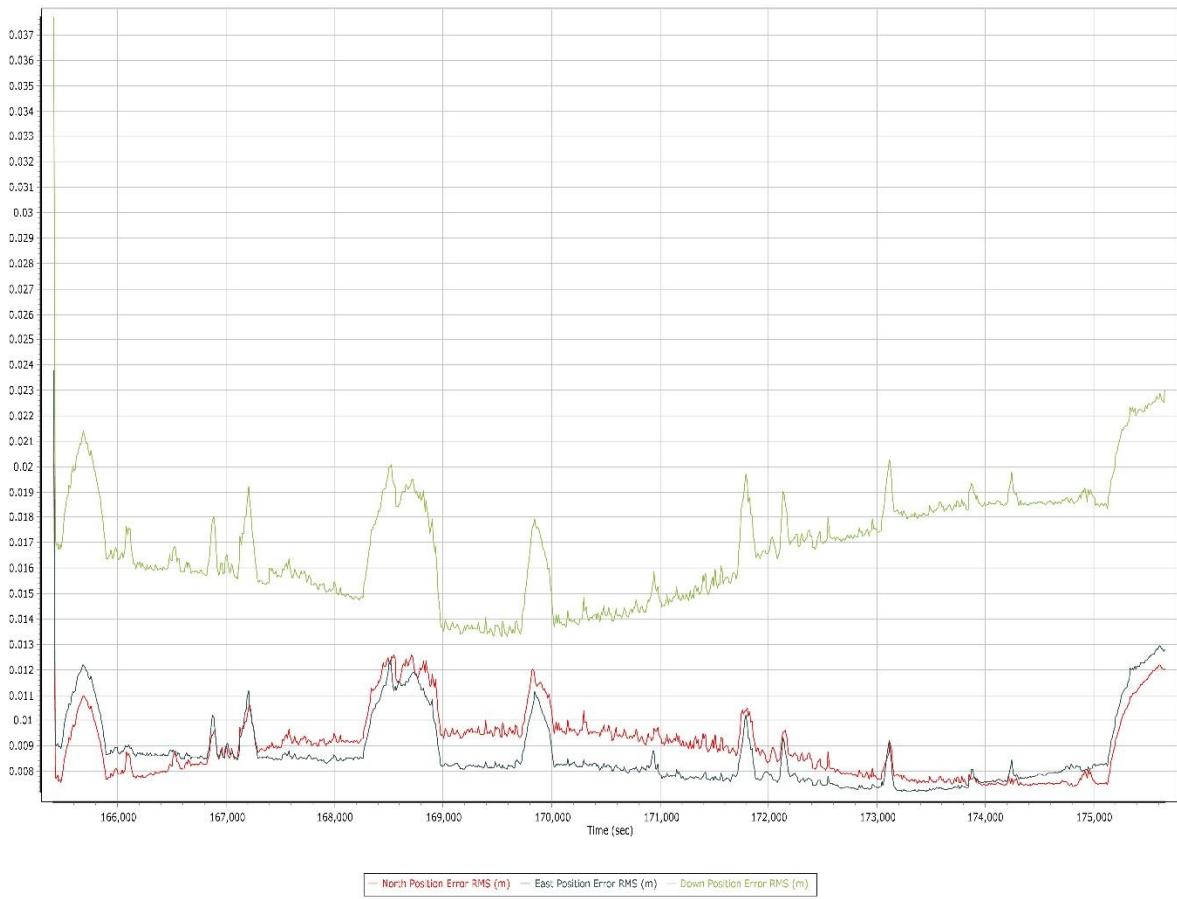


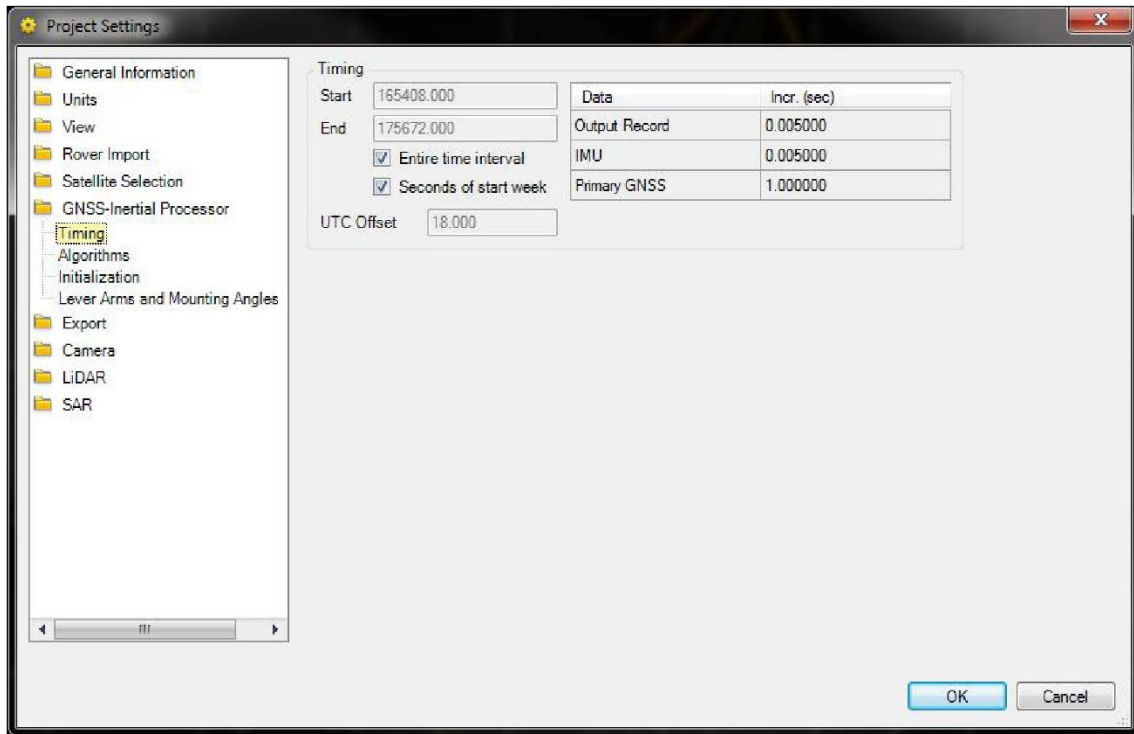


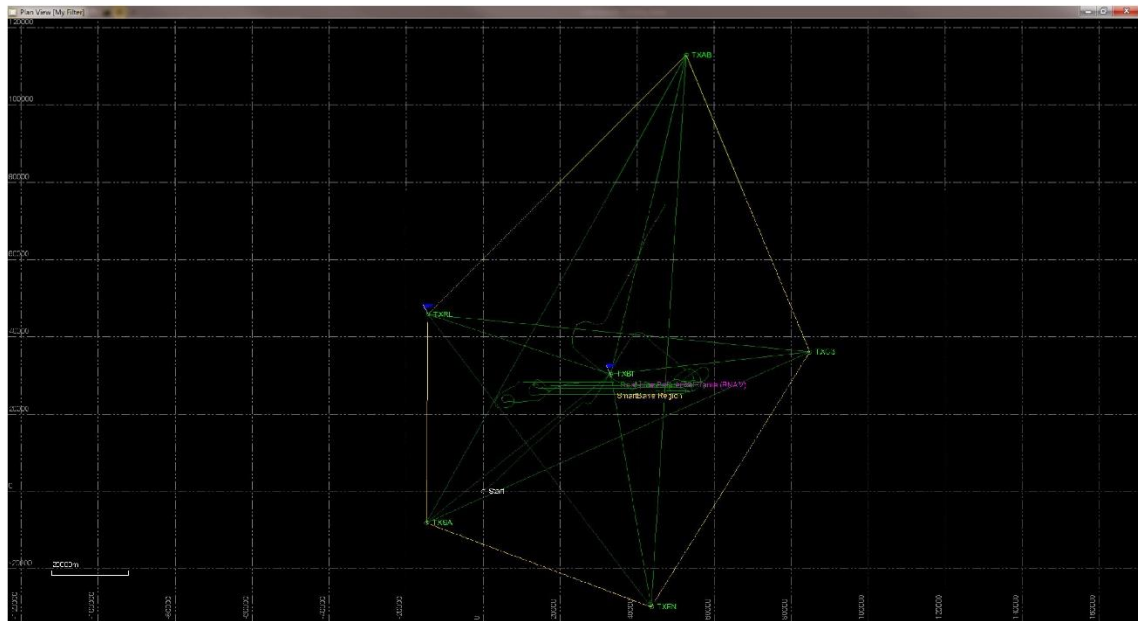


0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IA*PPF, 6 = C/A, 7 = GNSS Nav, 8 = DR

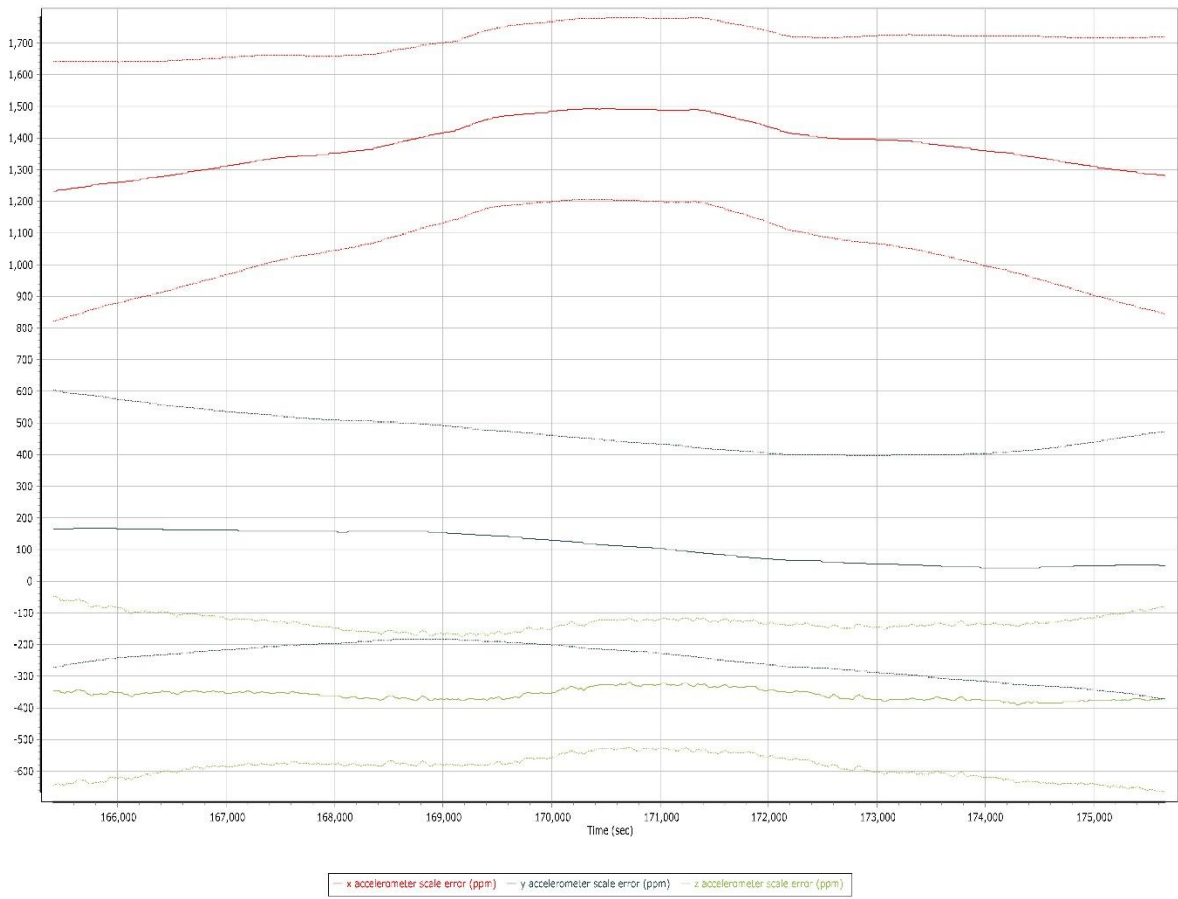


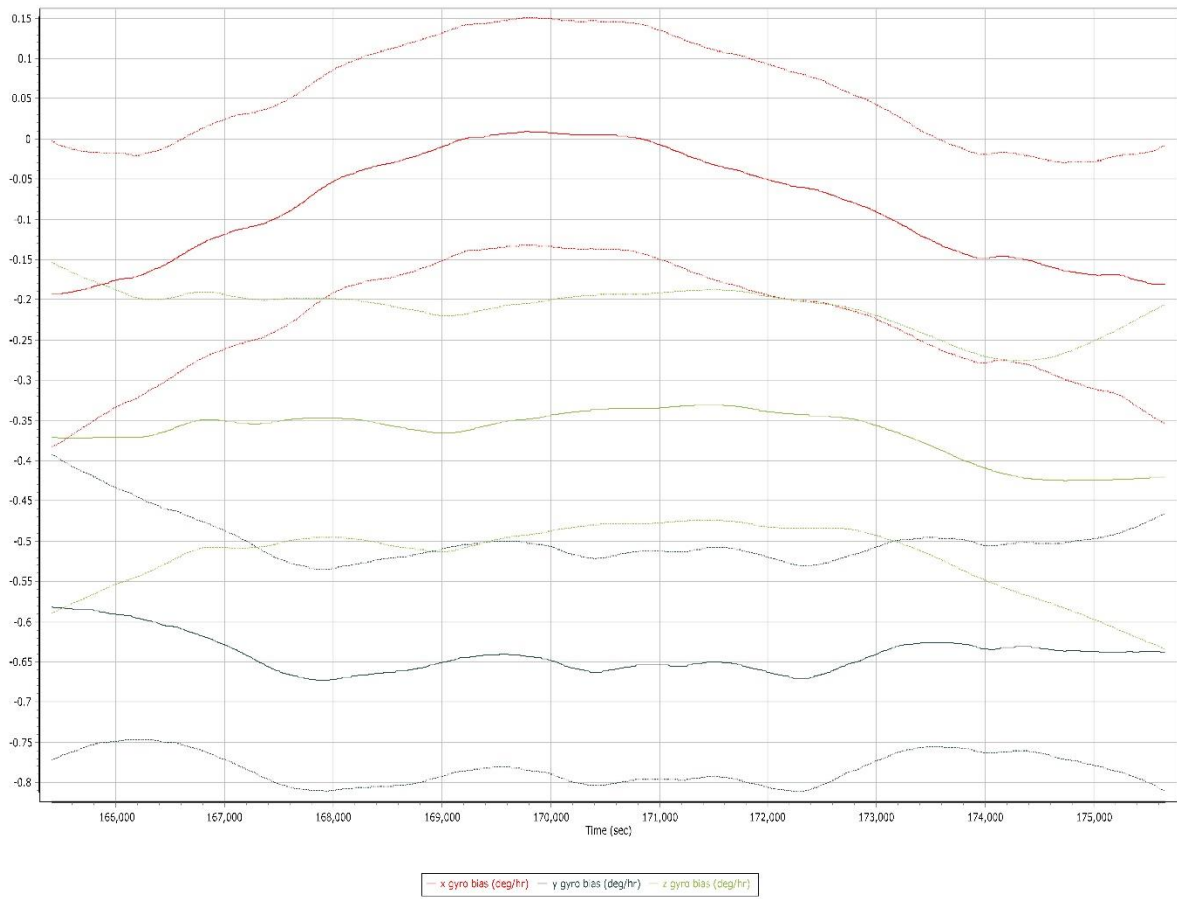


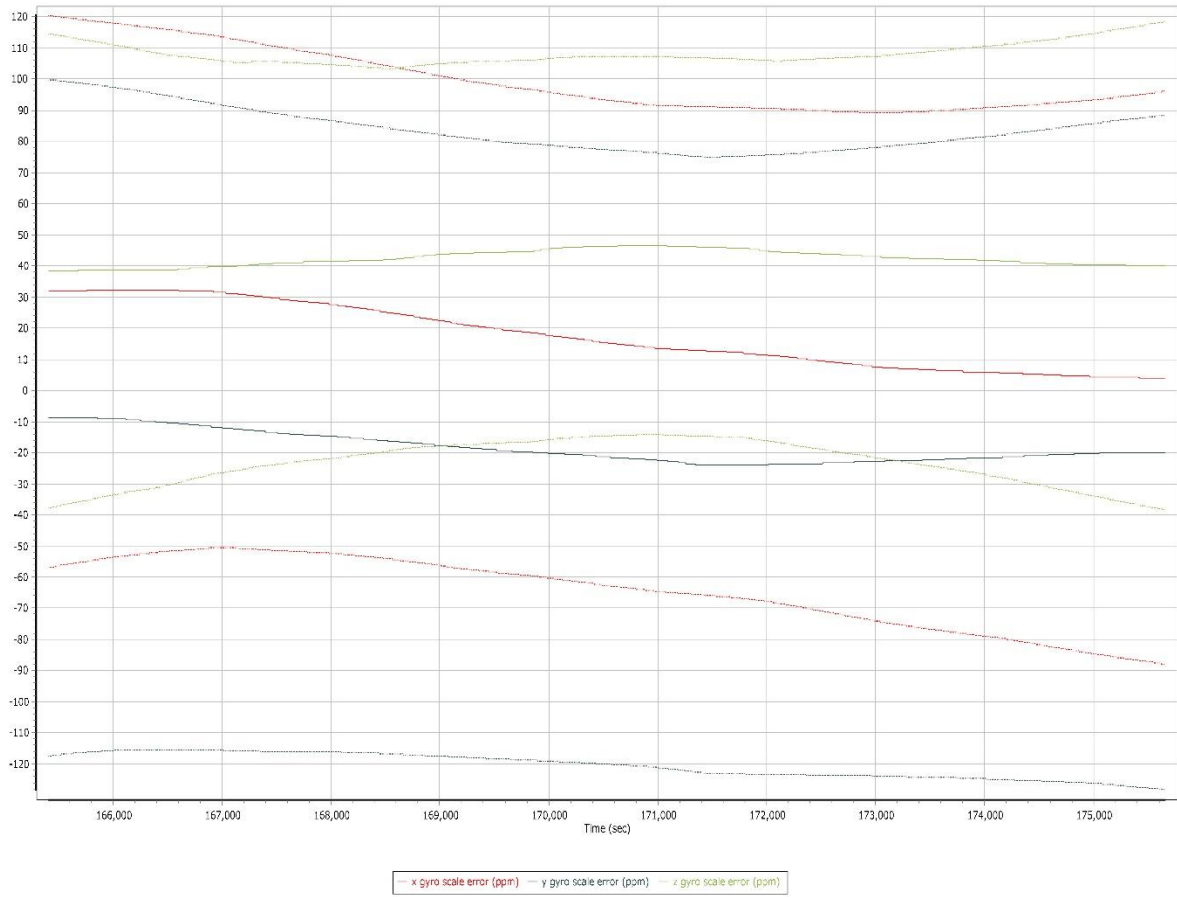




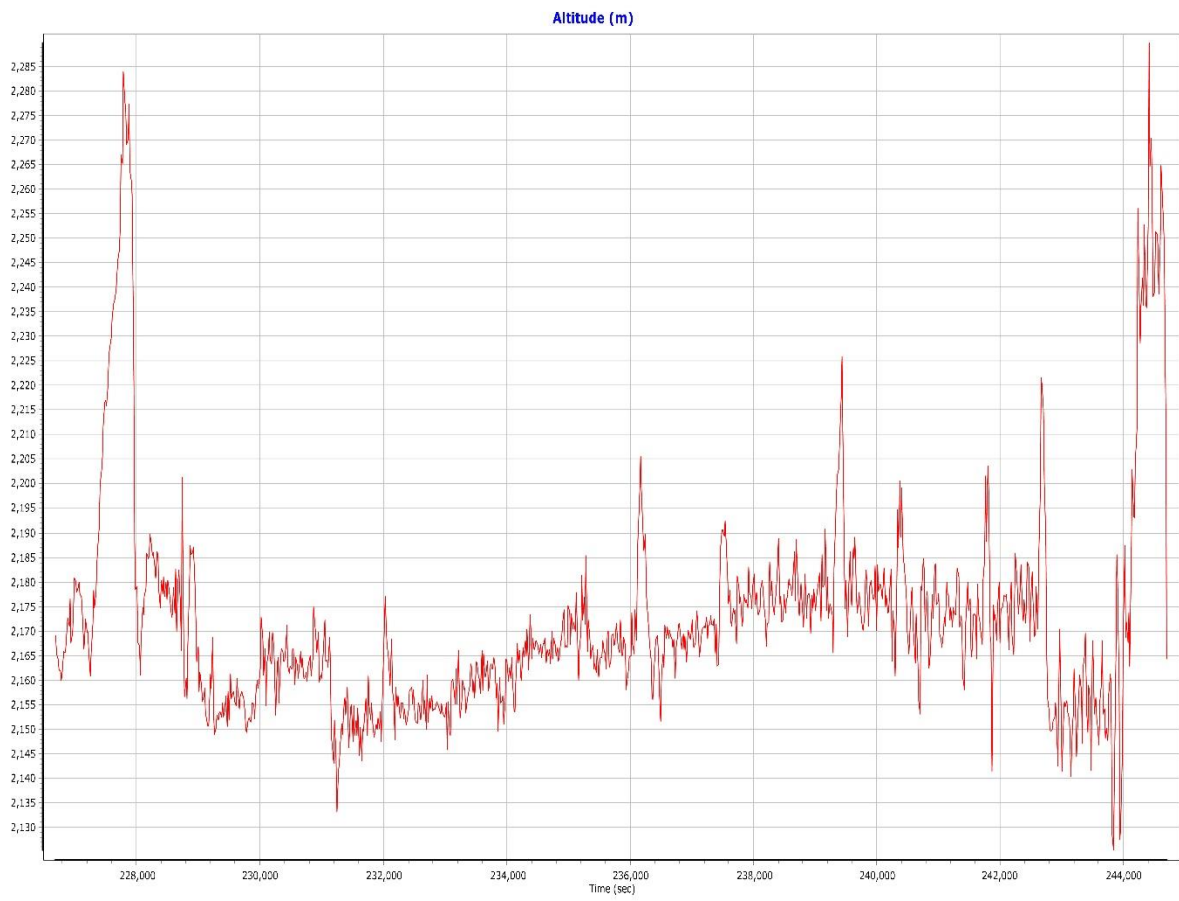


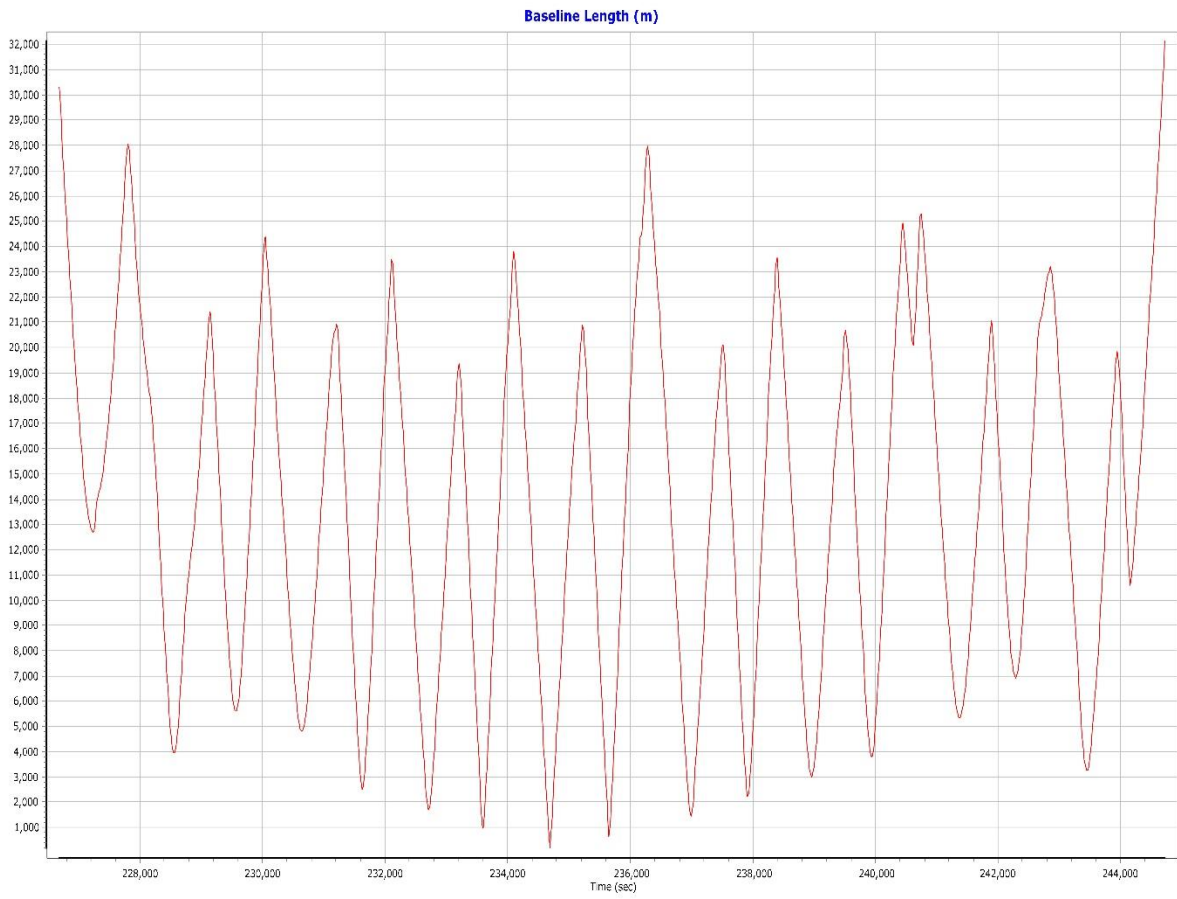


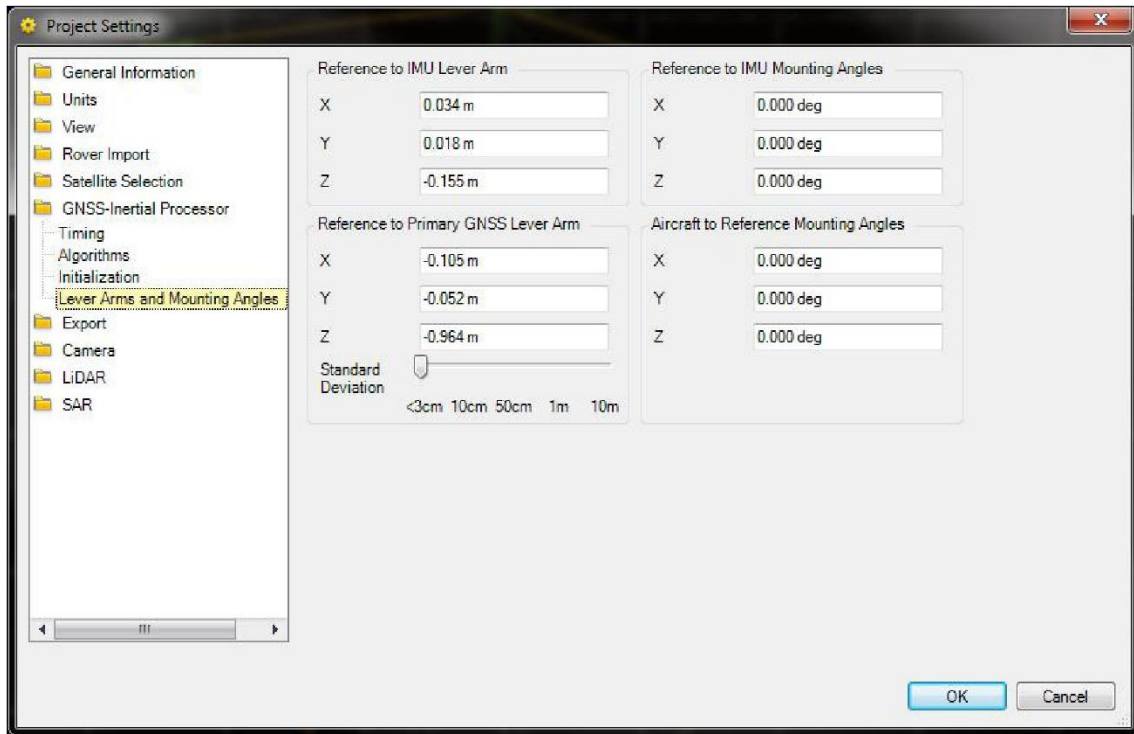


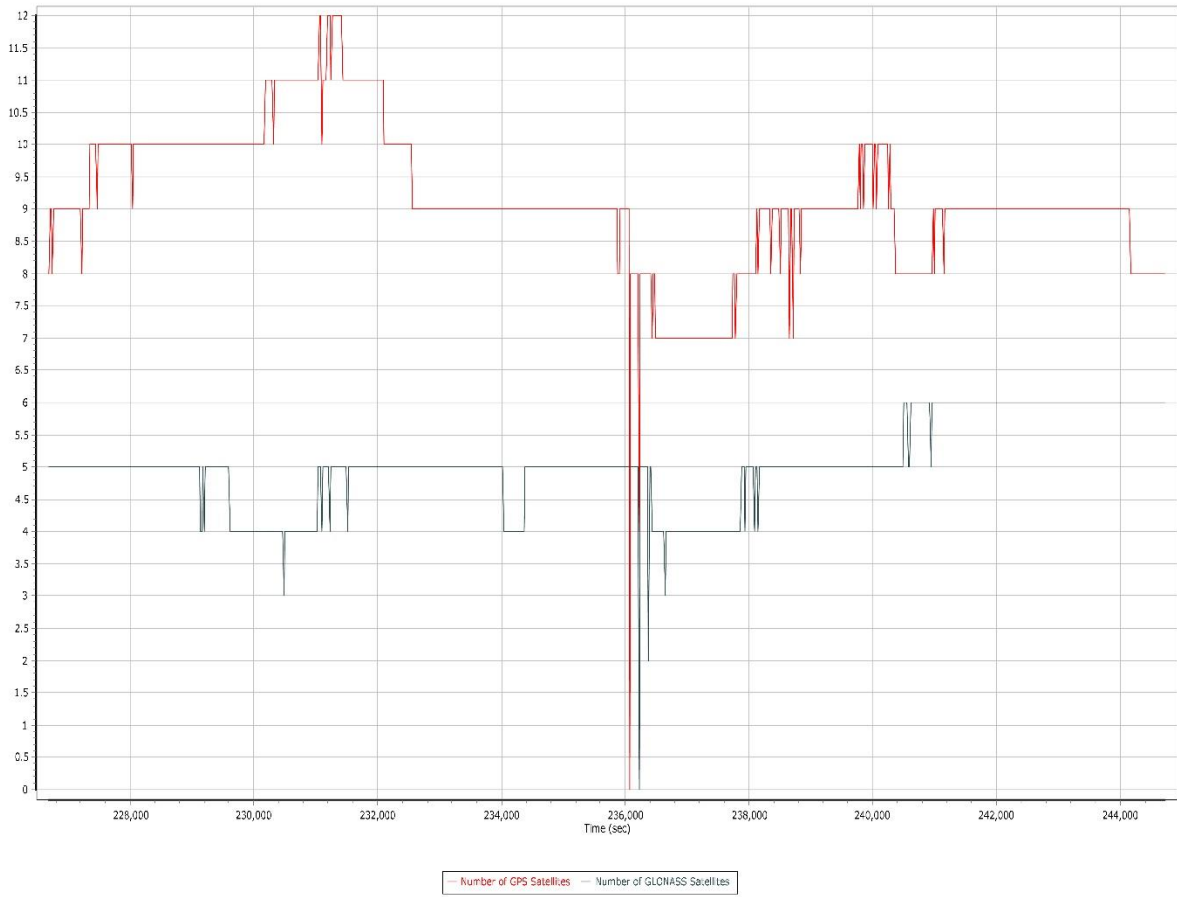


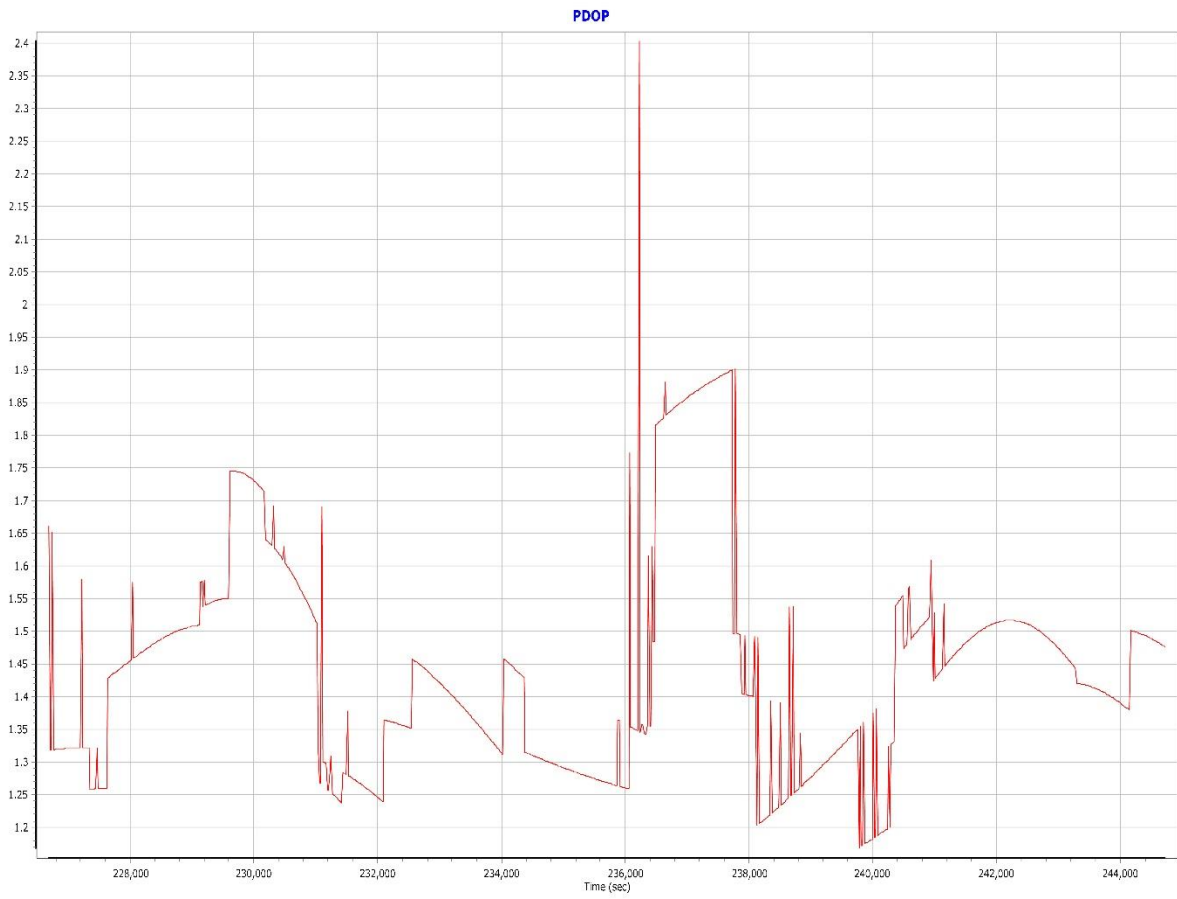
UNB18065A

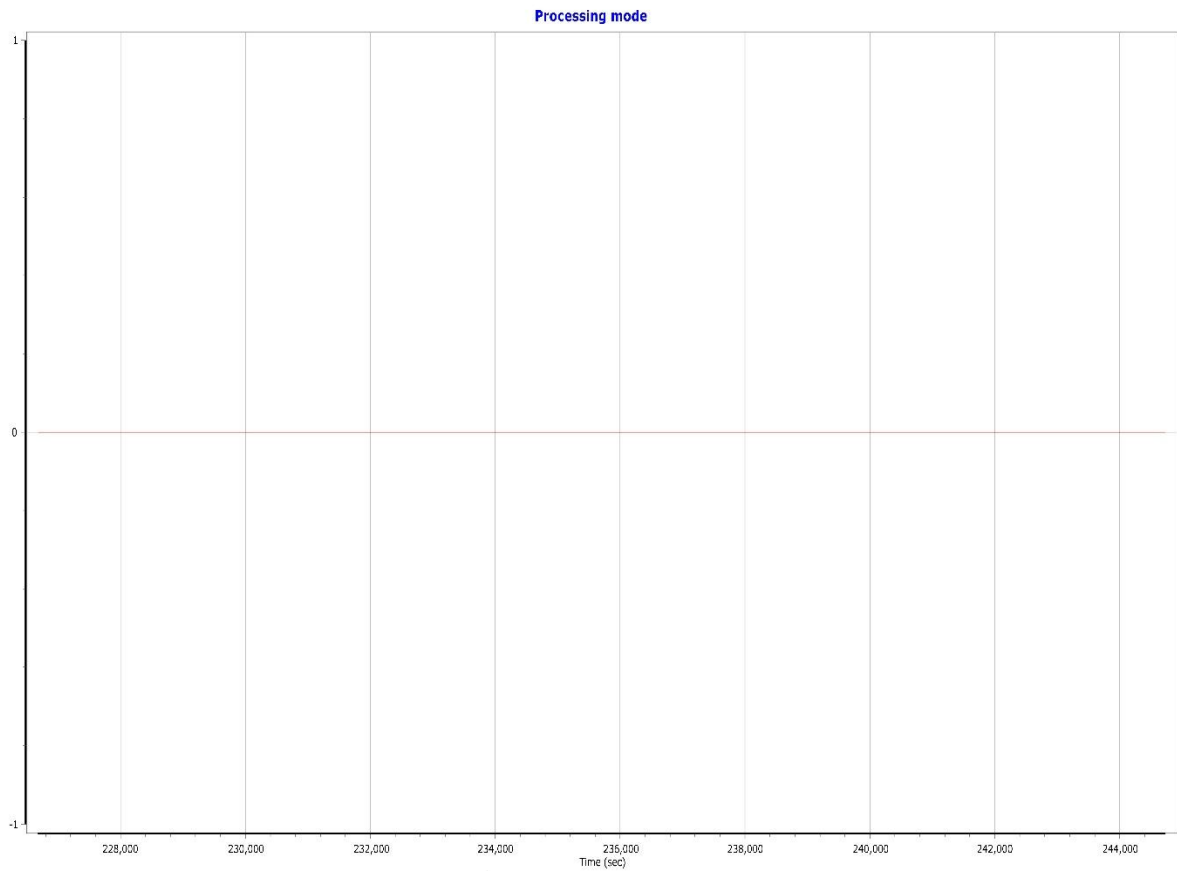




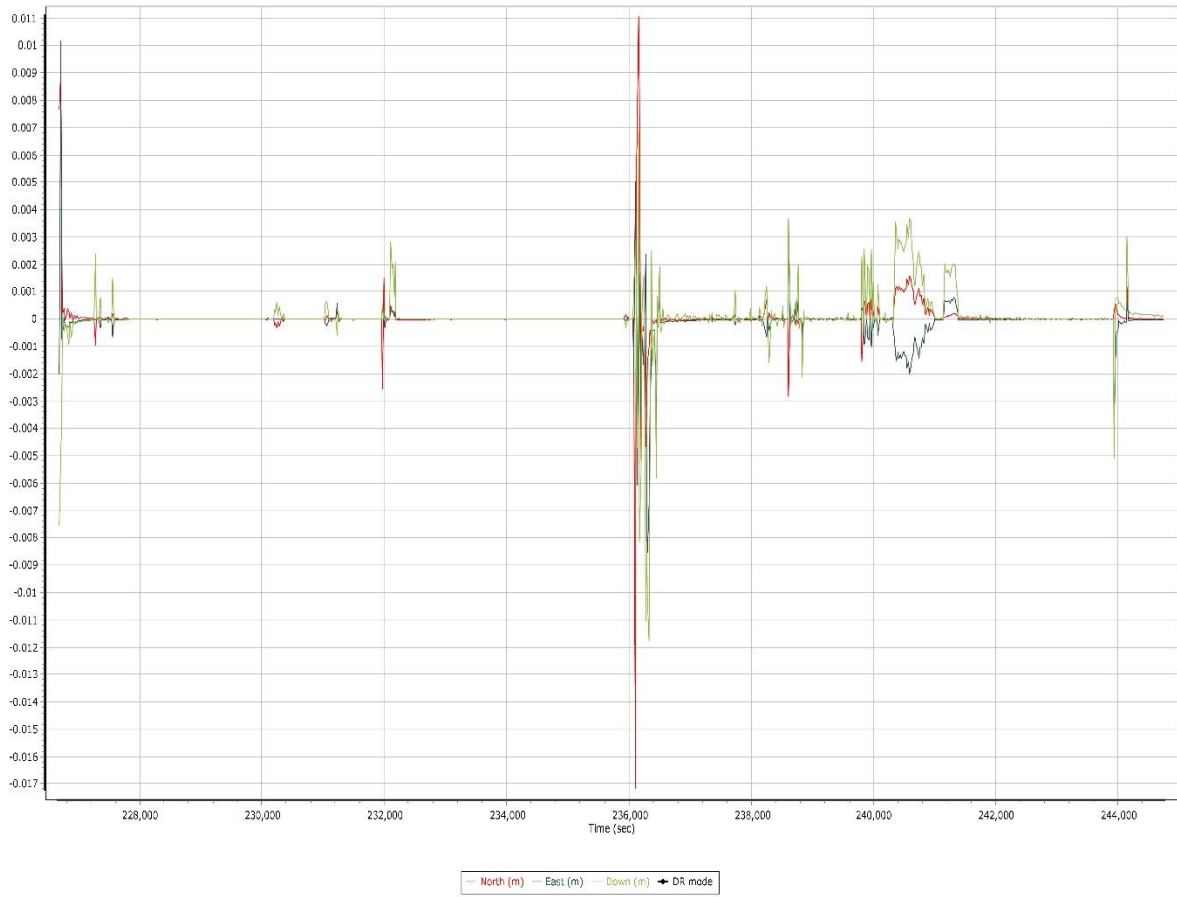


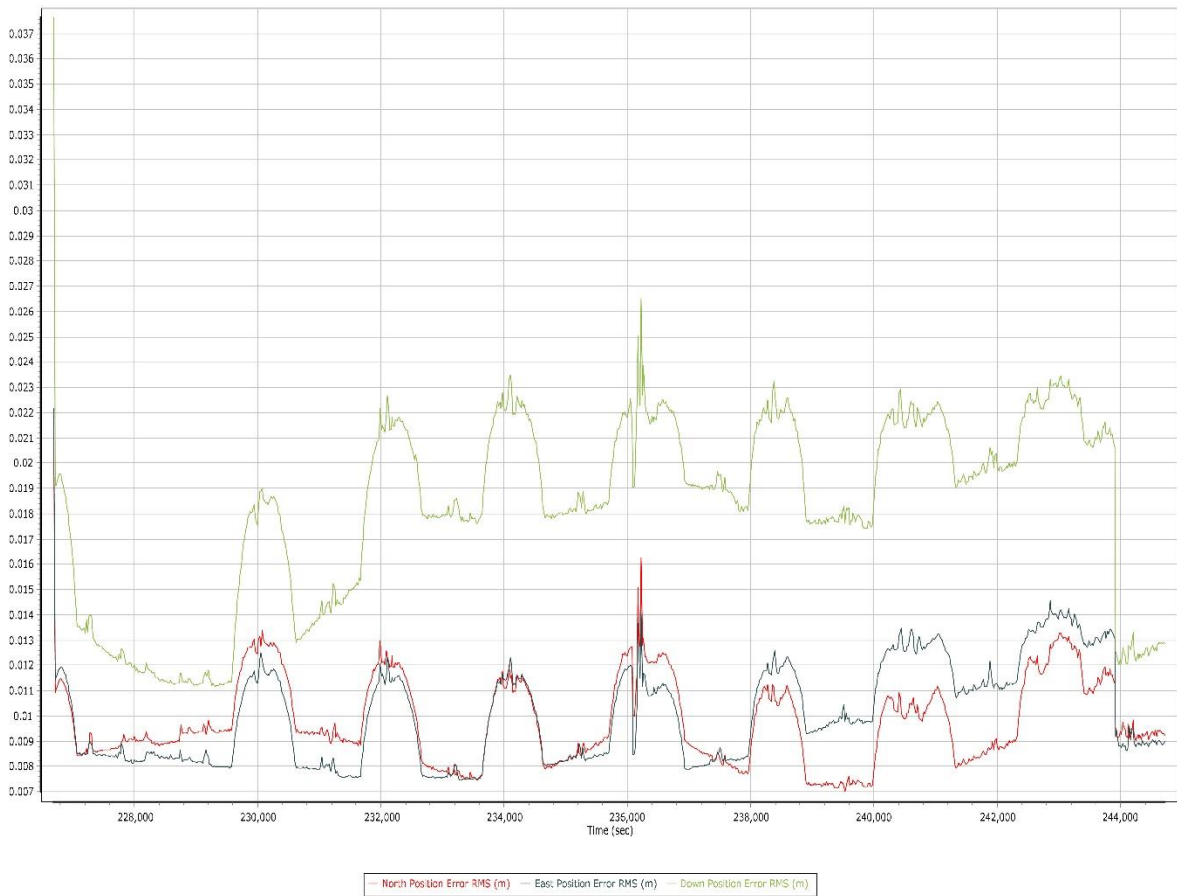


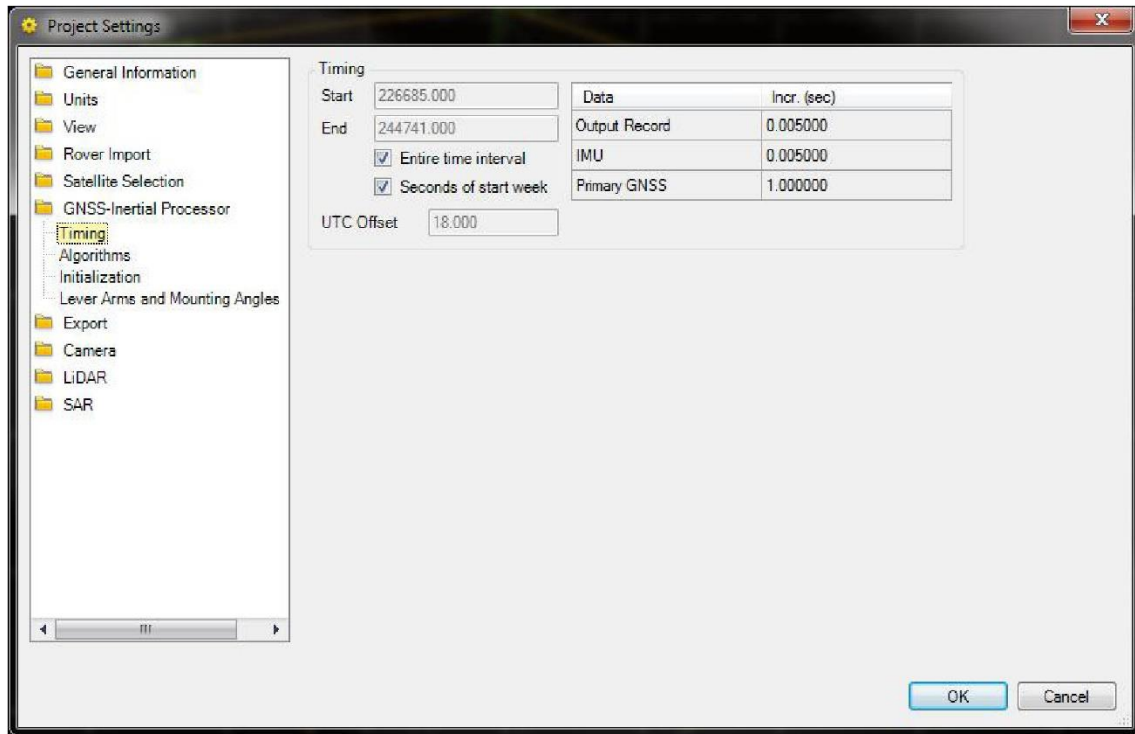


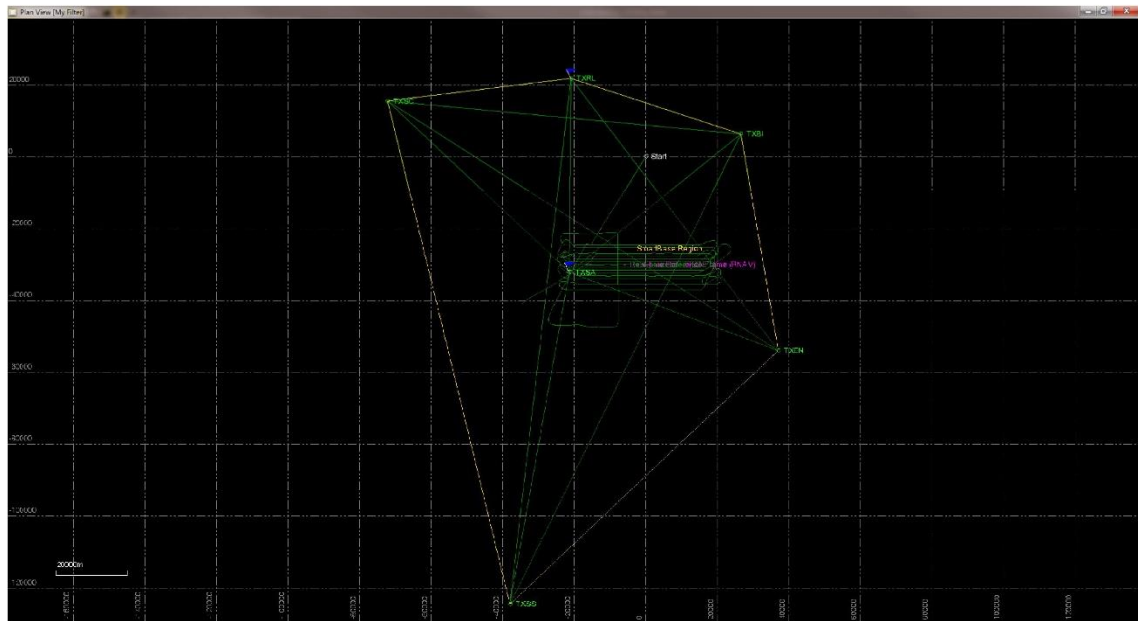


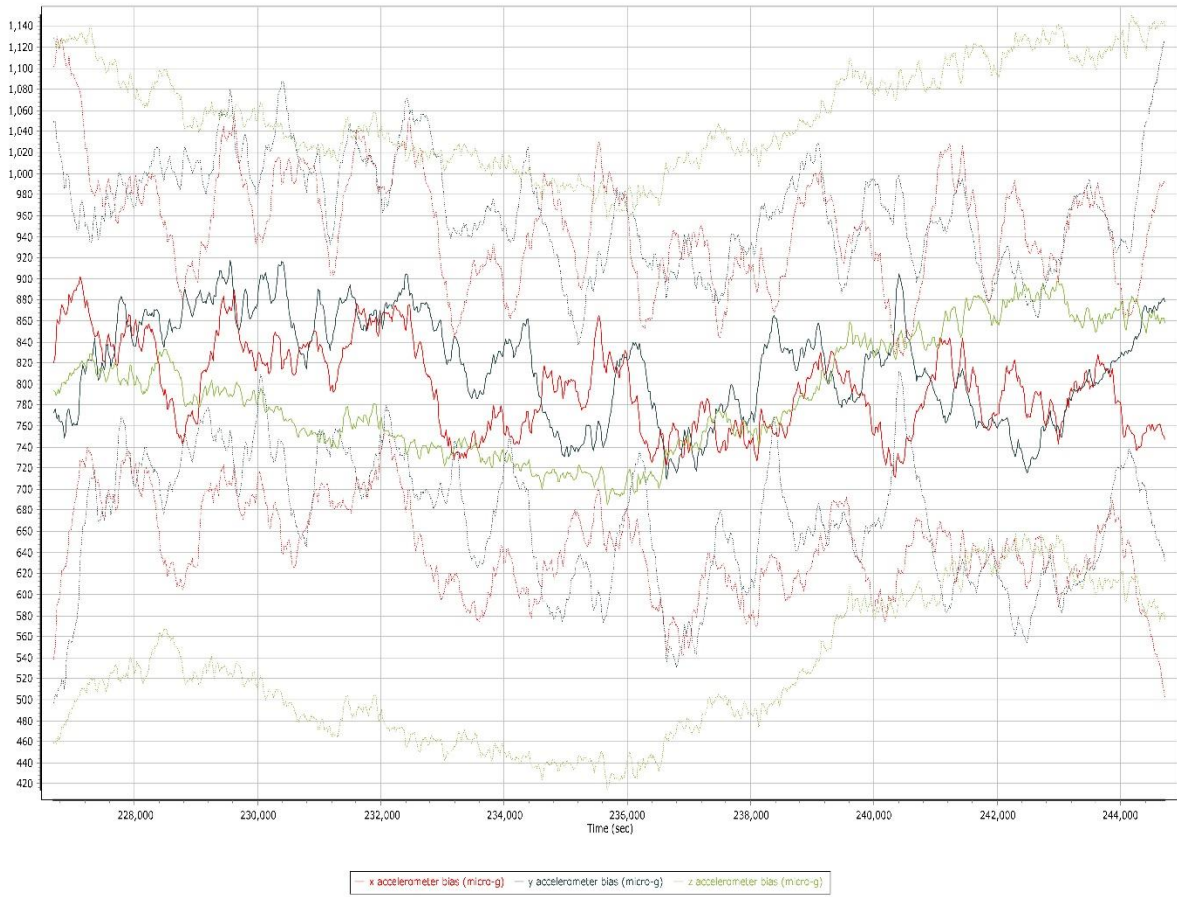
0 = Fixed NL, 1 = Fixed WL, 2 = Float, 3 = DGNSS, 4 = RTCM, 5 = IA PPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

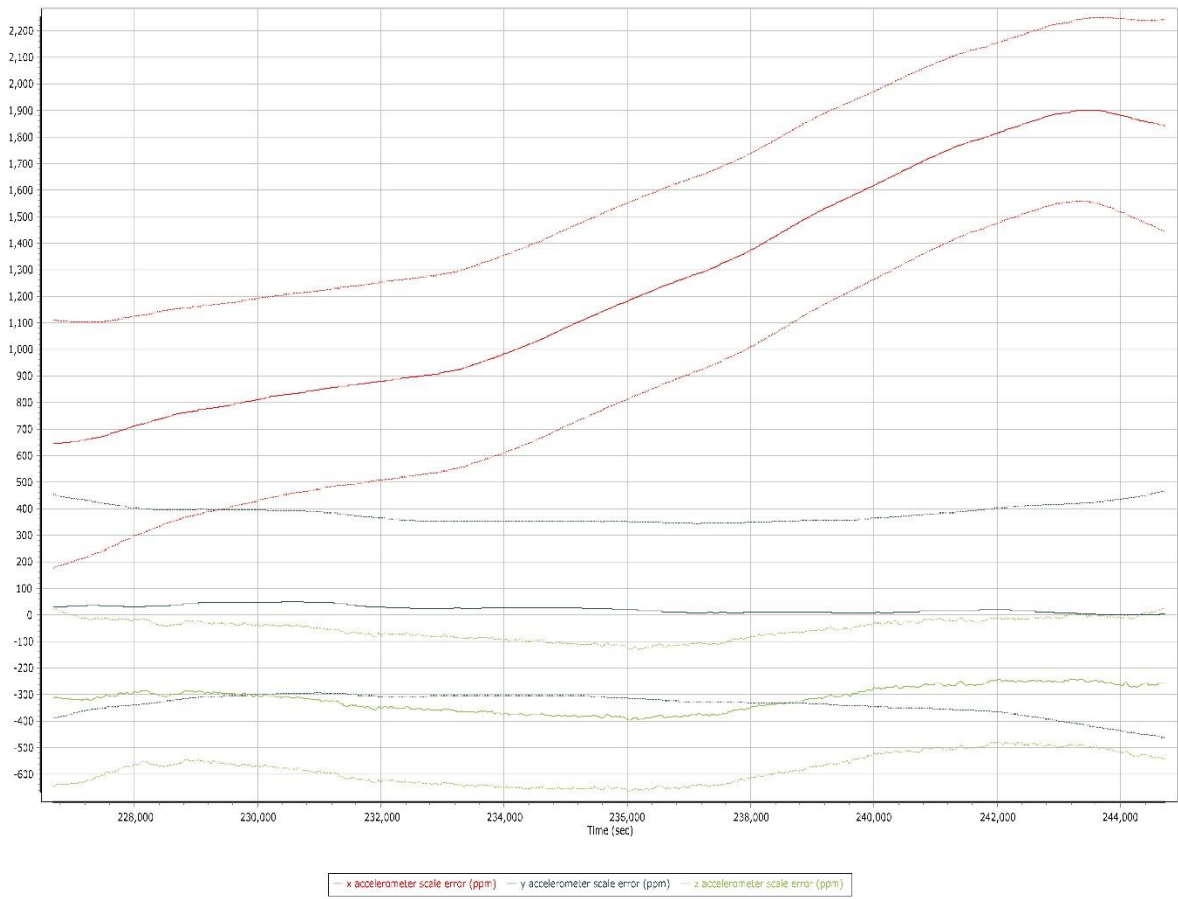


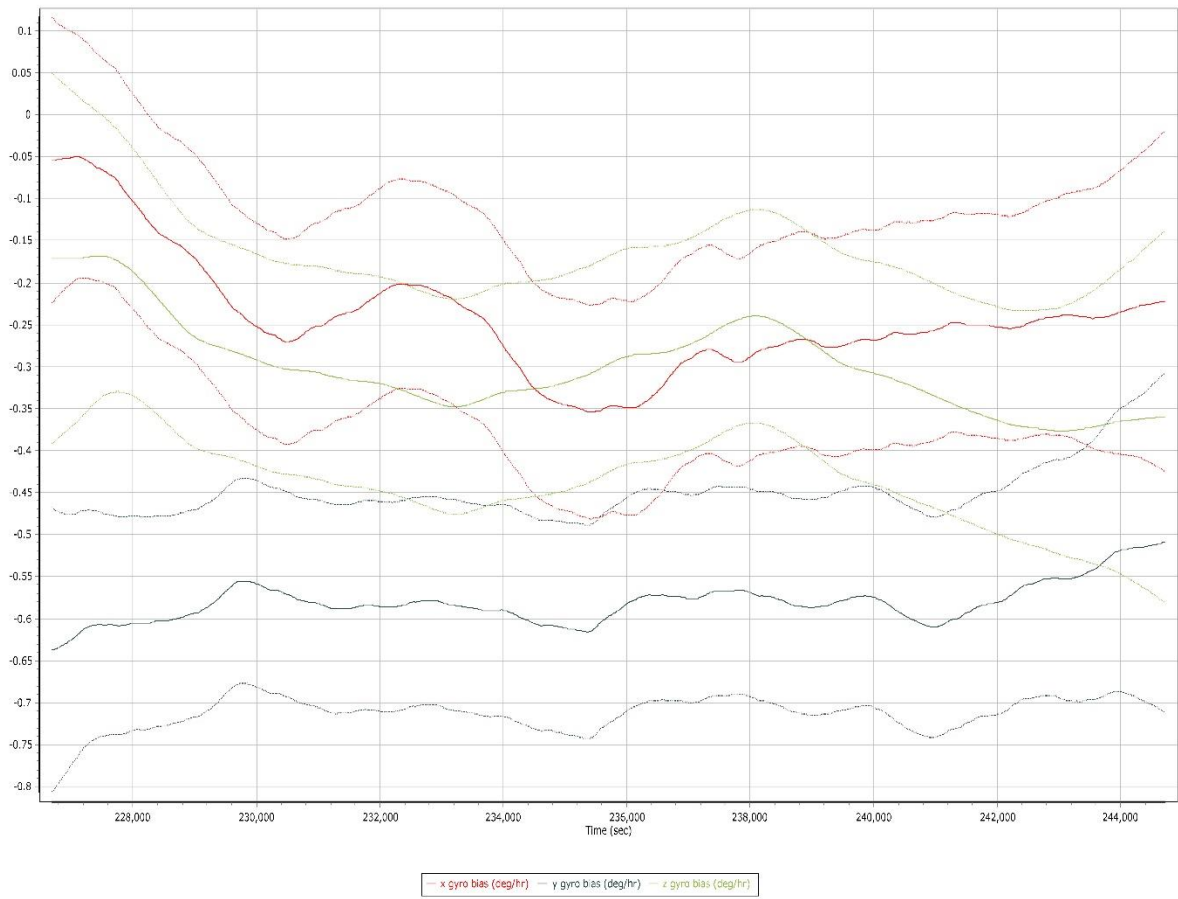


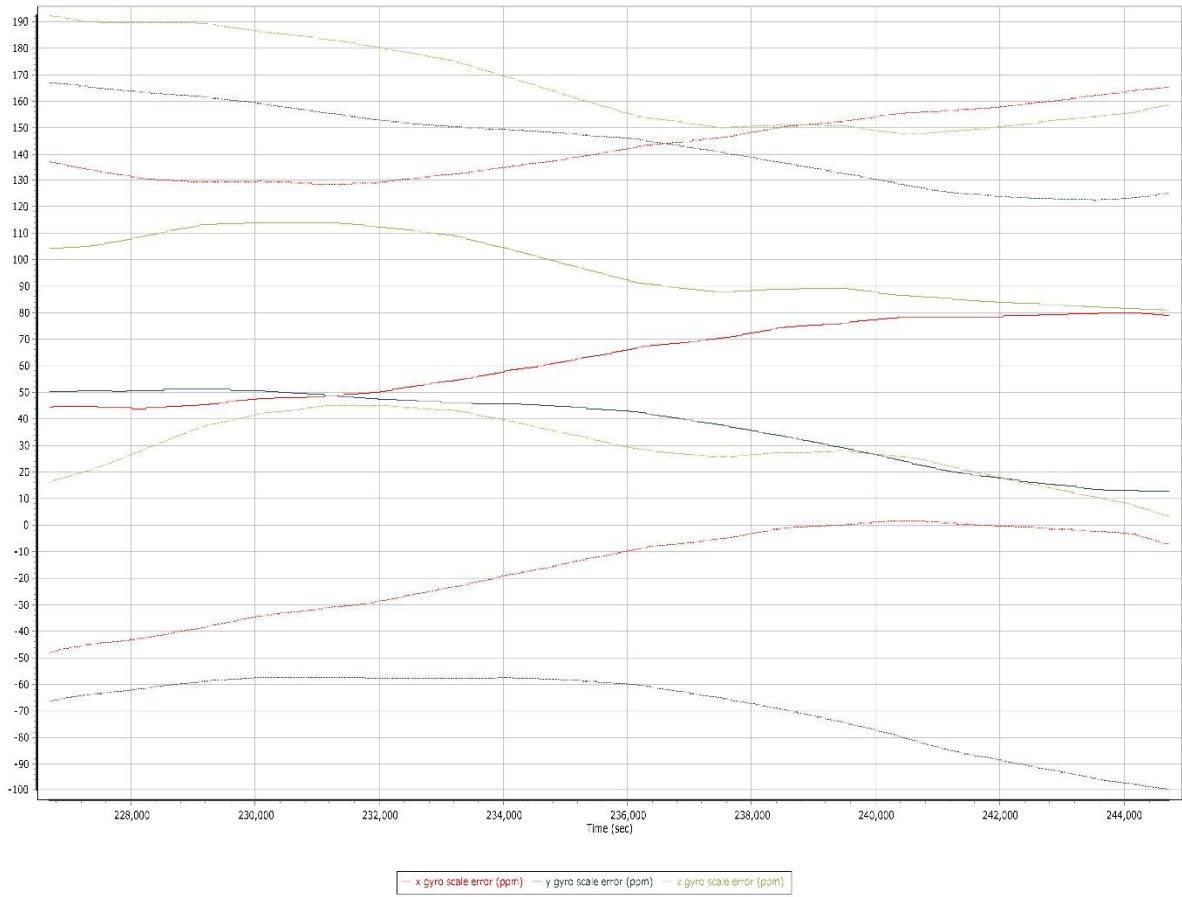




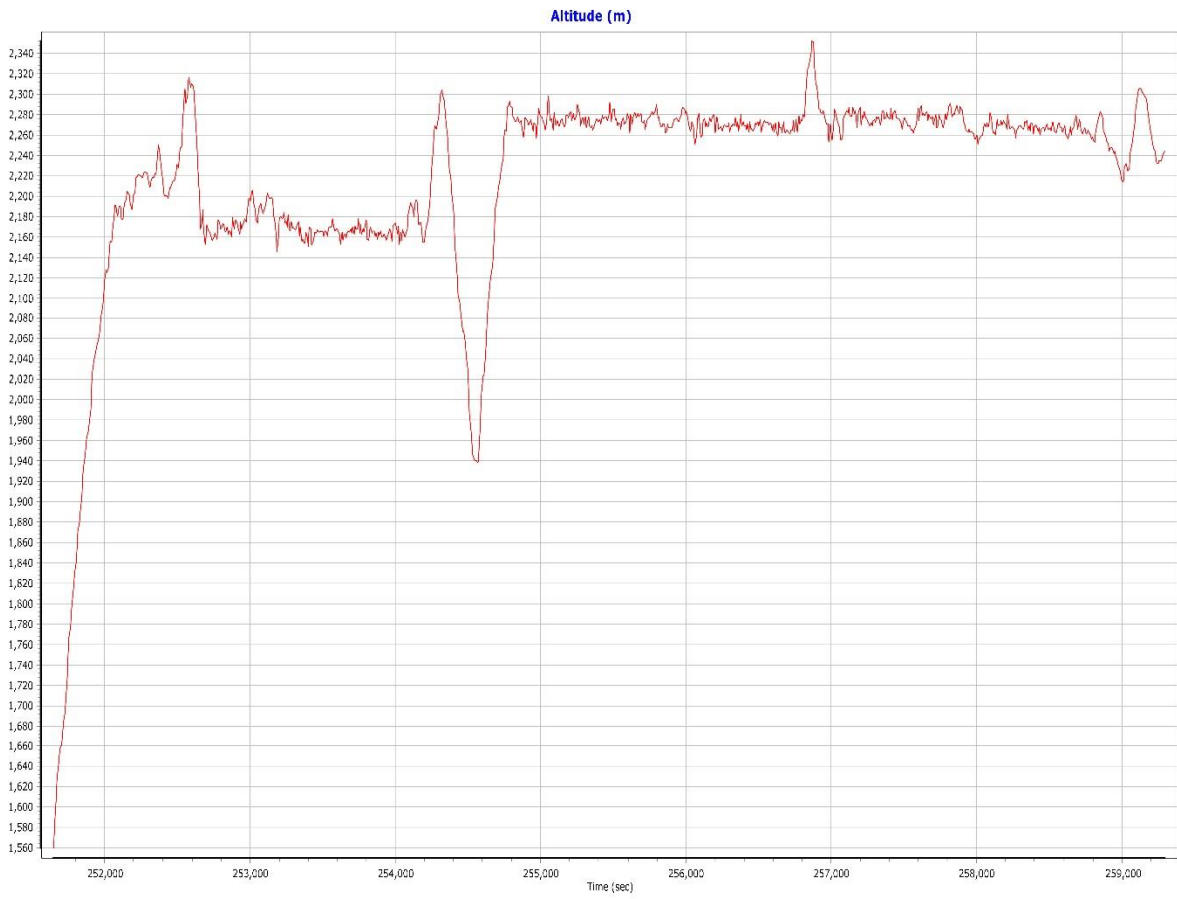


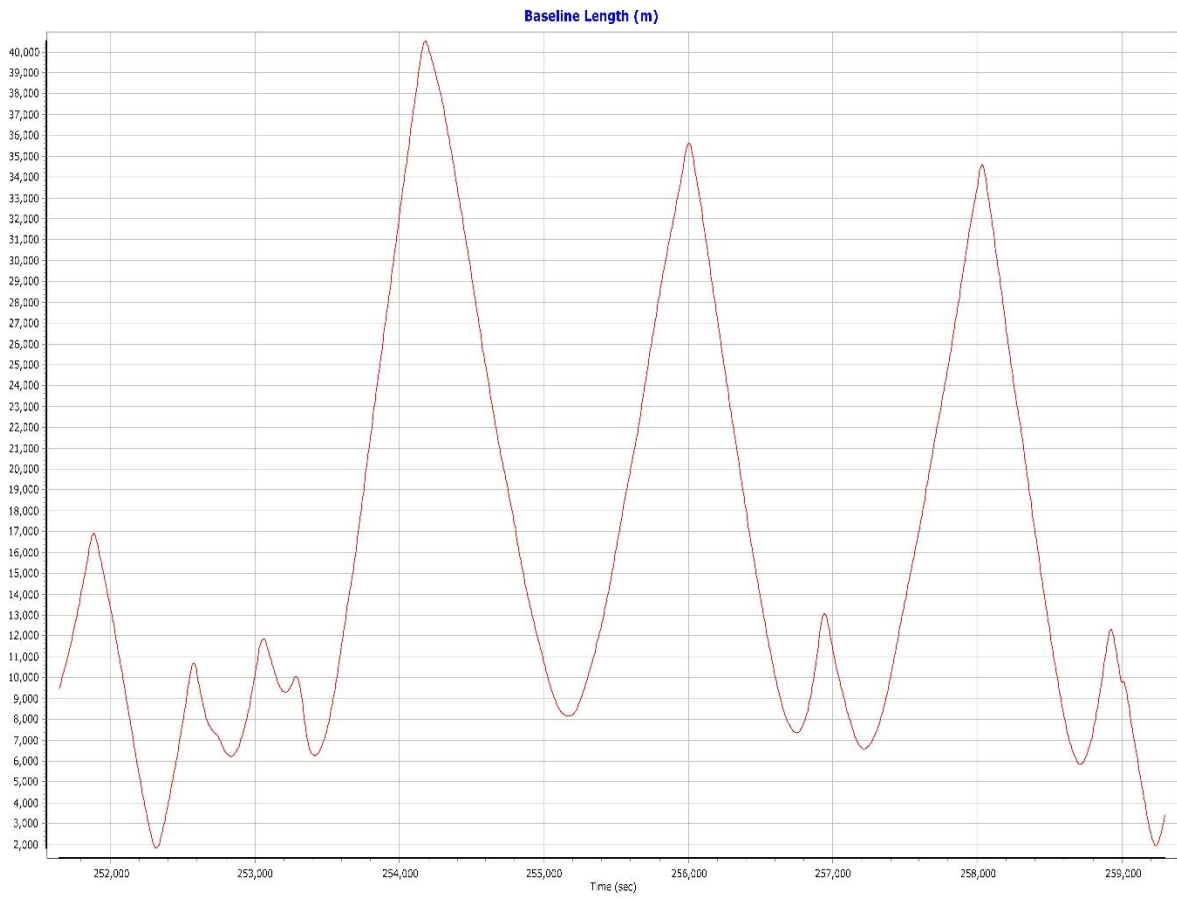


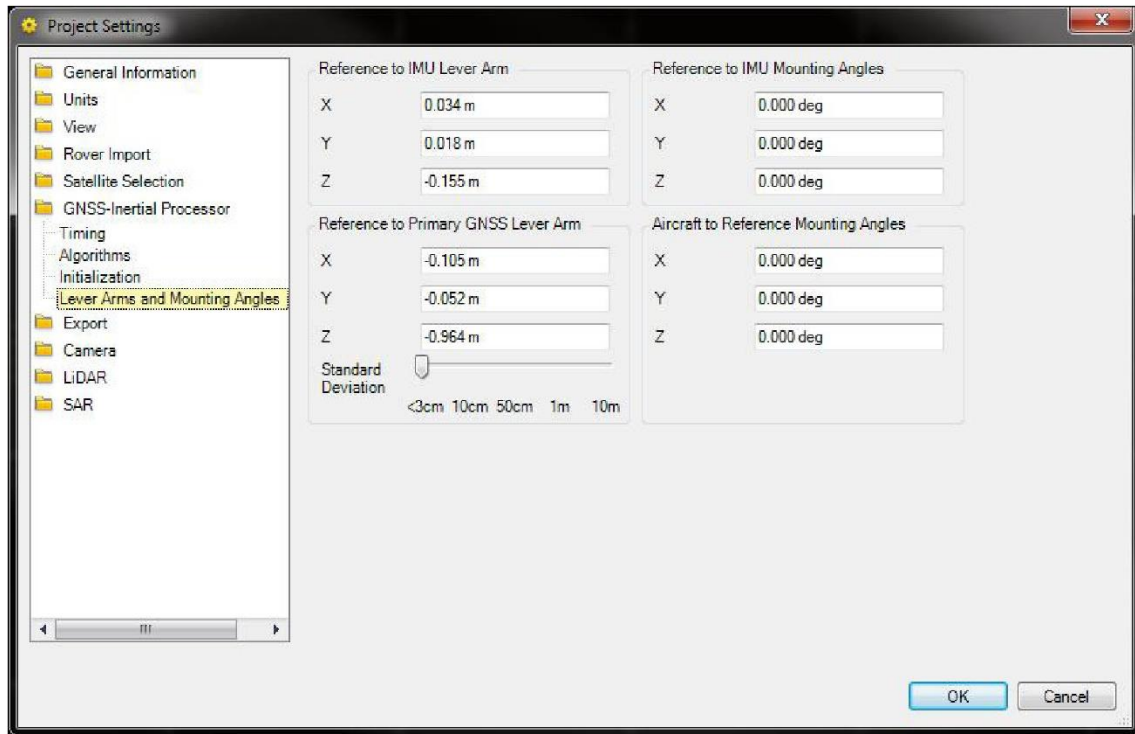


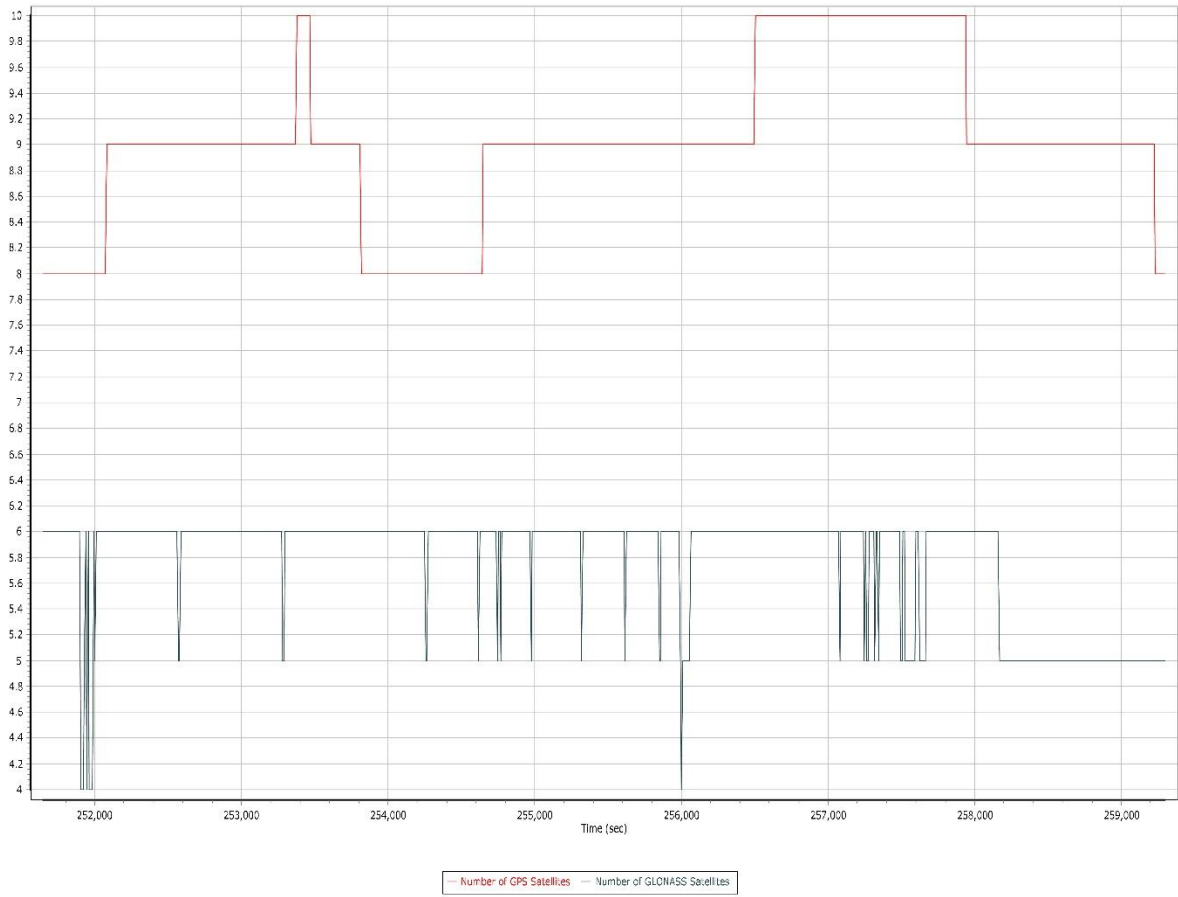


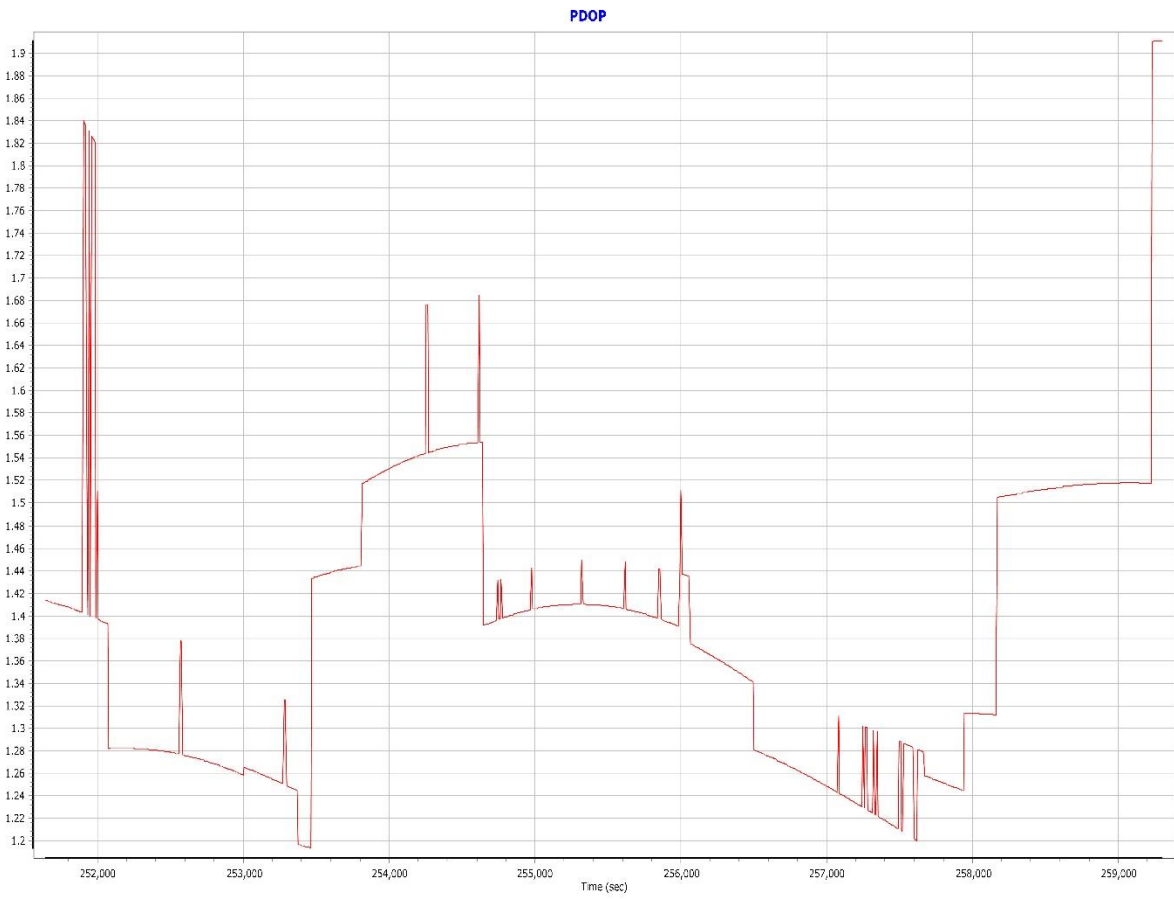
UNB18065B

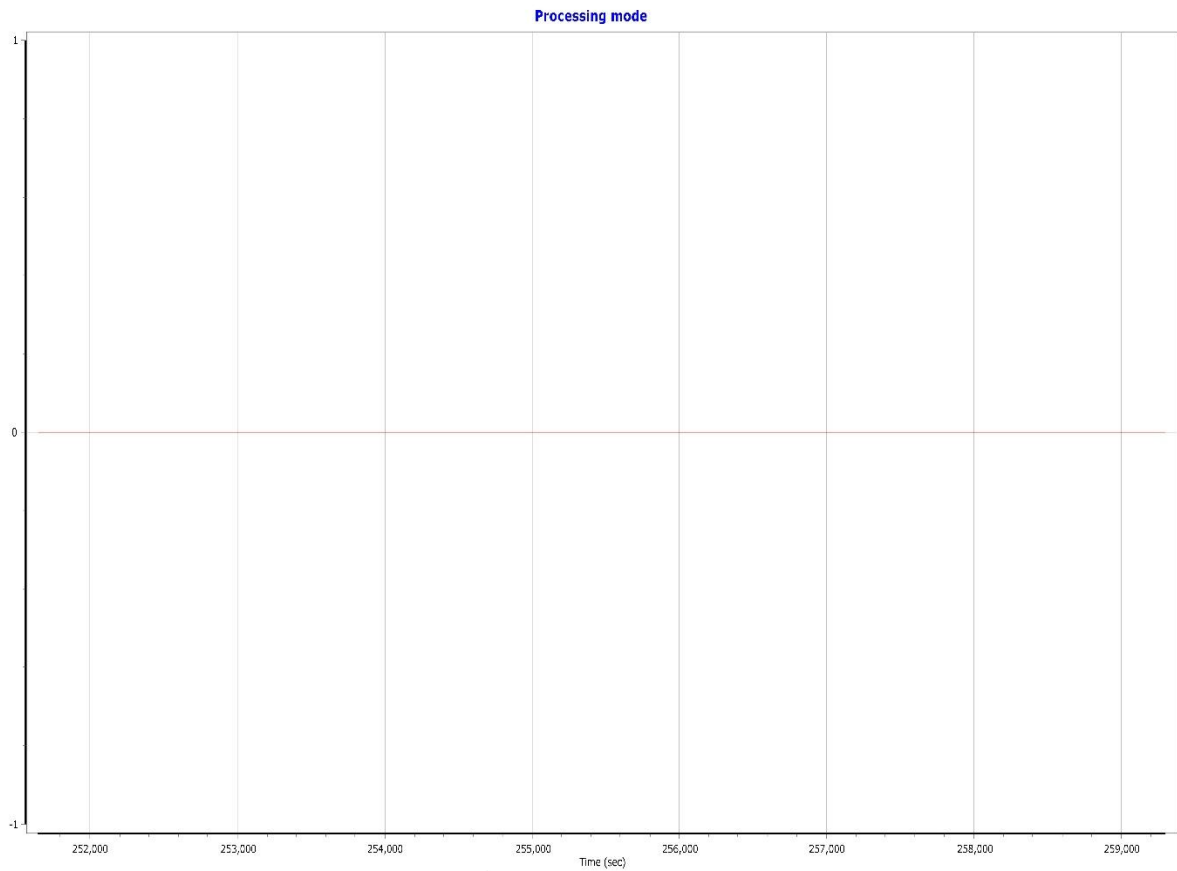




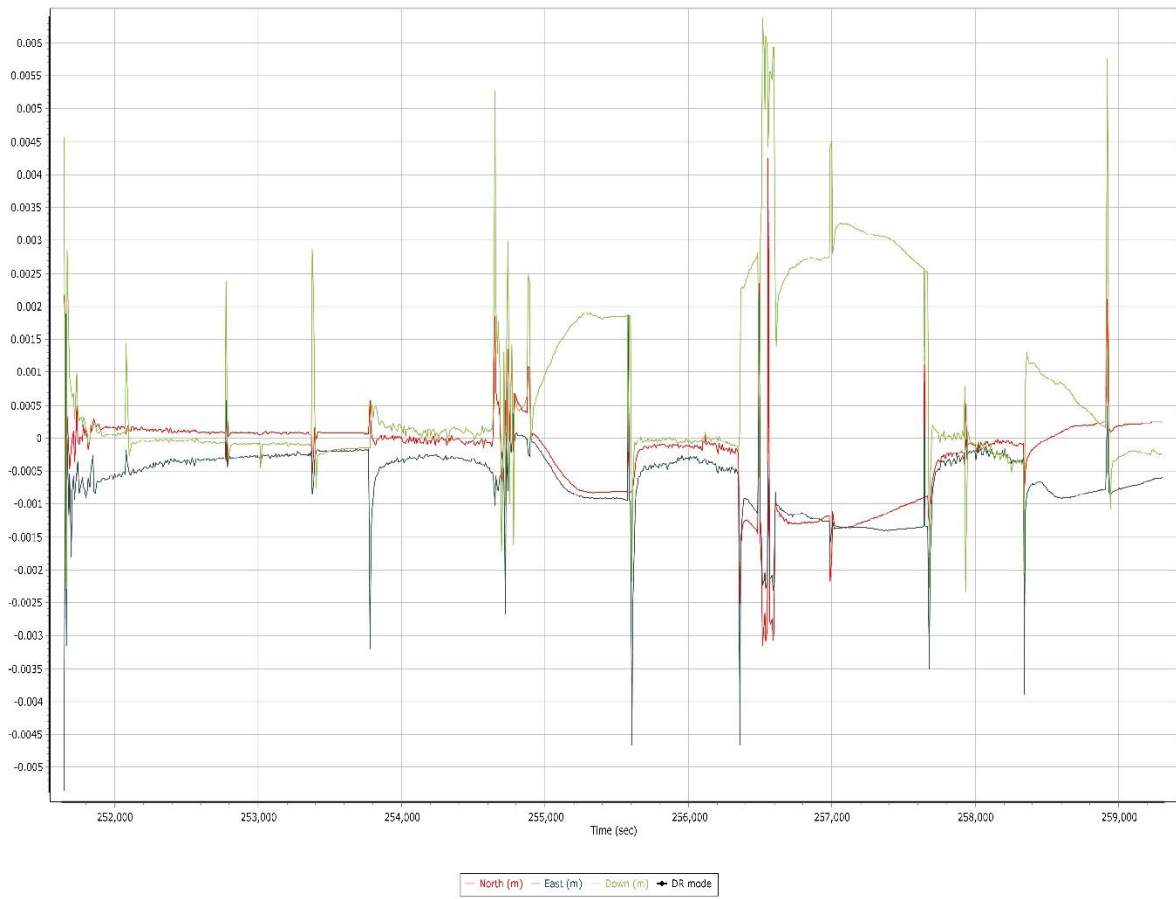


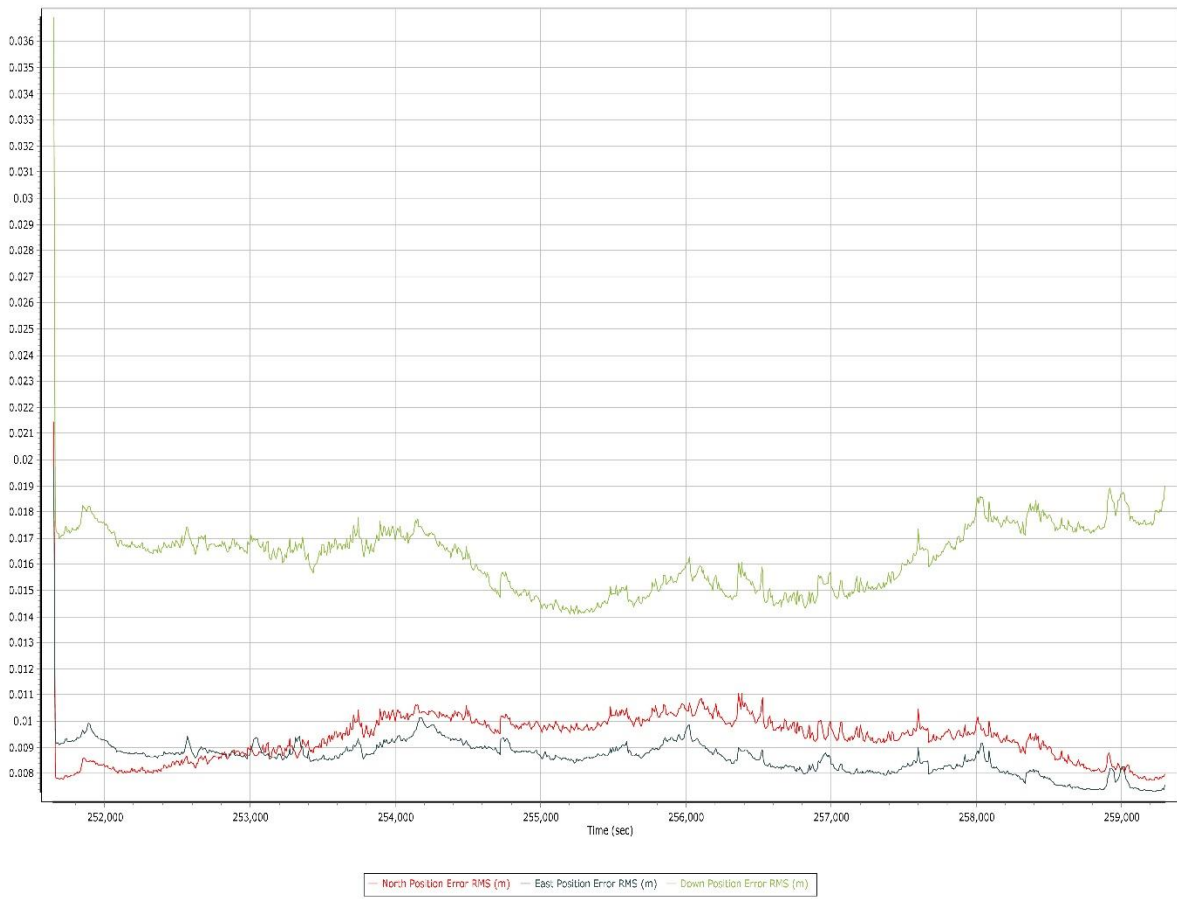


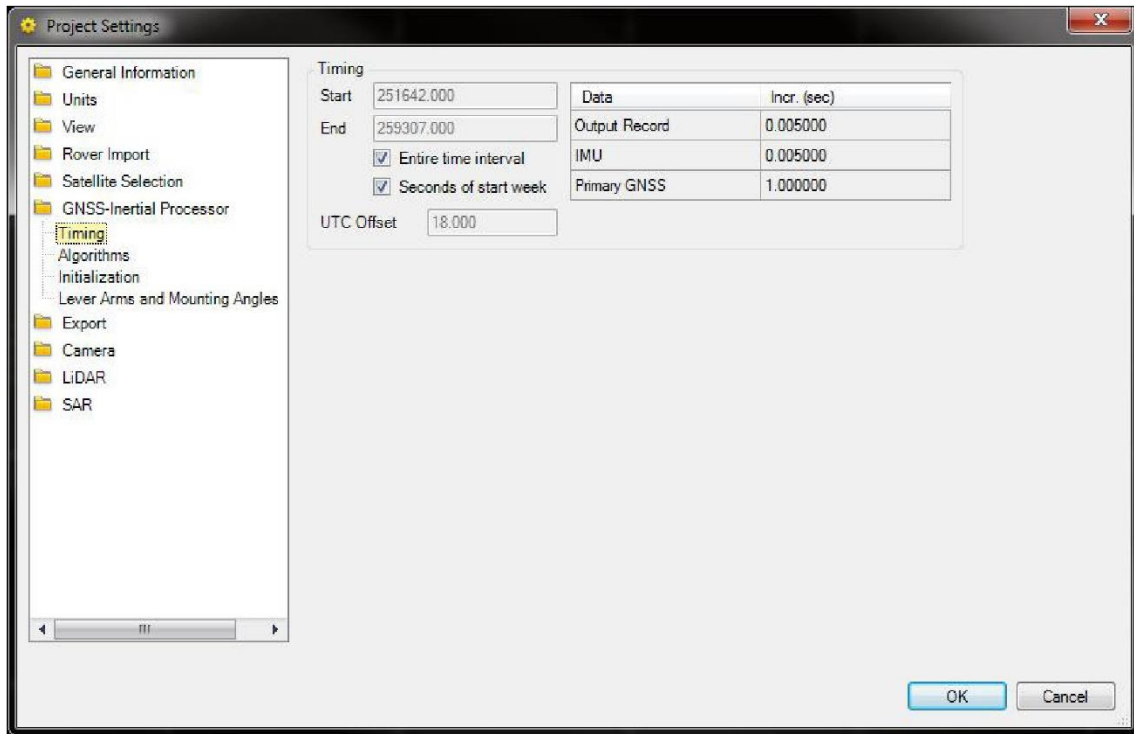


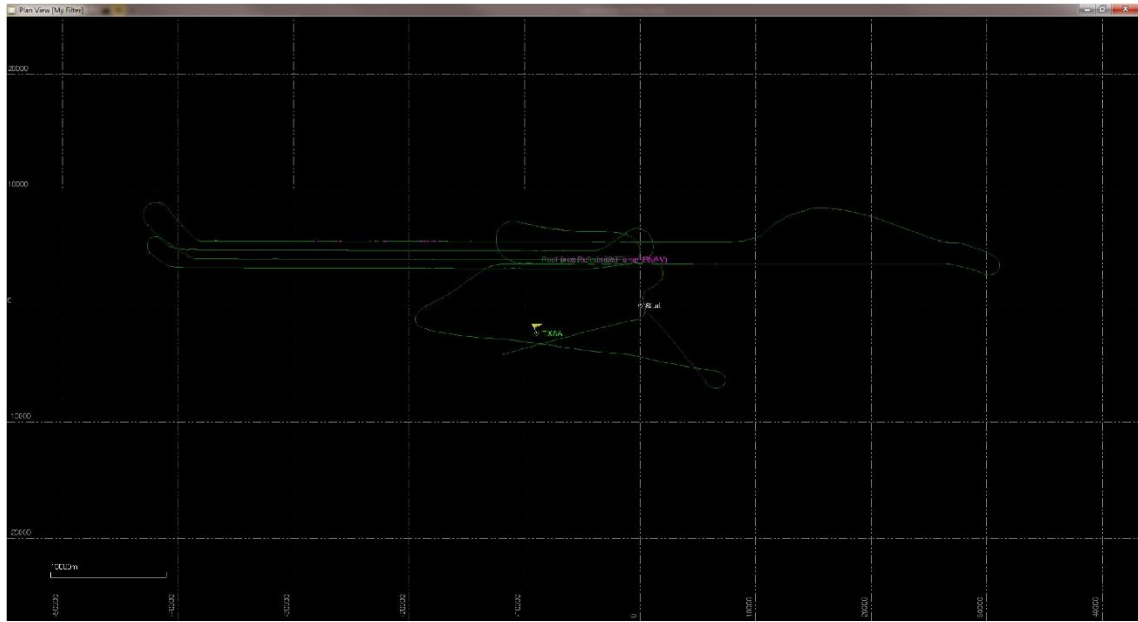


0 = Fixed NL, 1 = fixed WL, 2 = float, 3 = DGNSS, 4 = RTCM, 5 = IA PPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

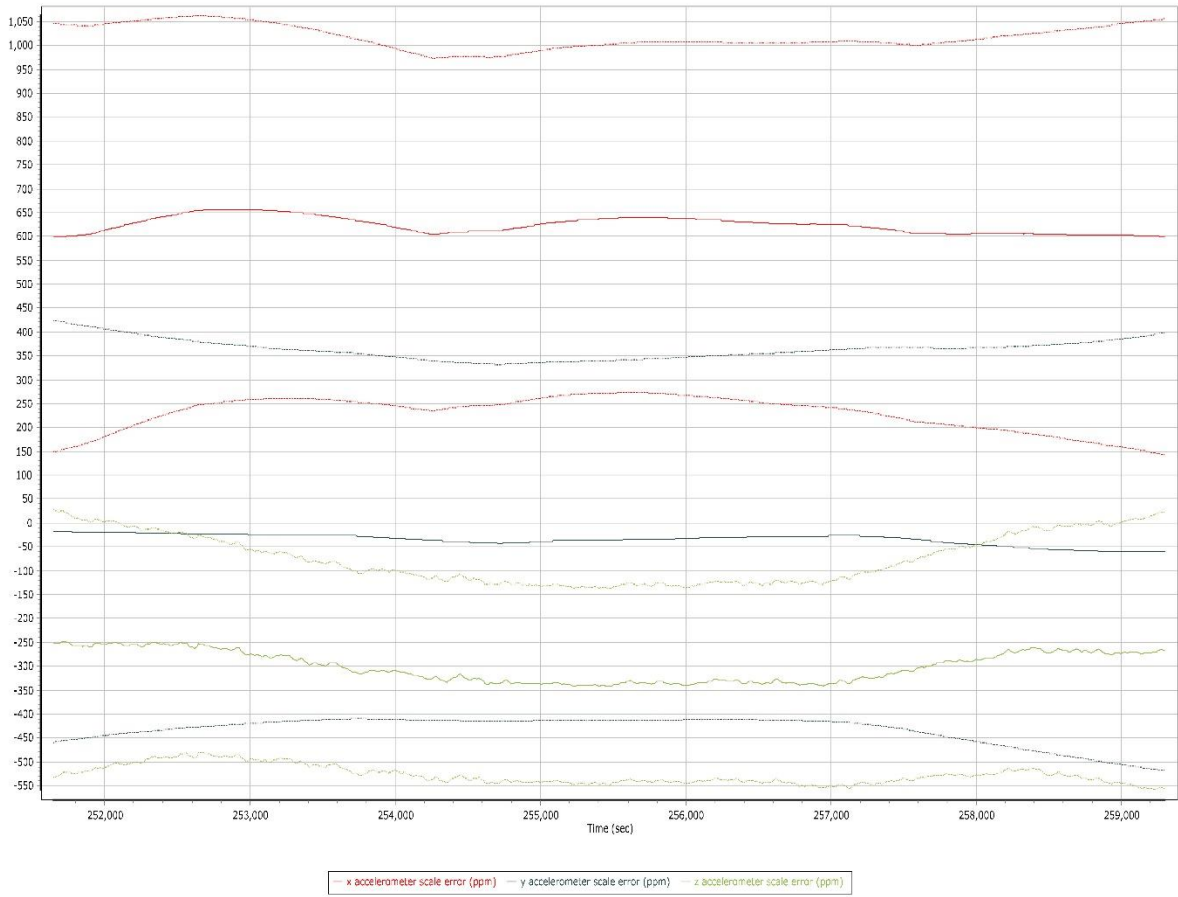


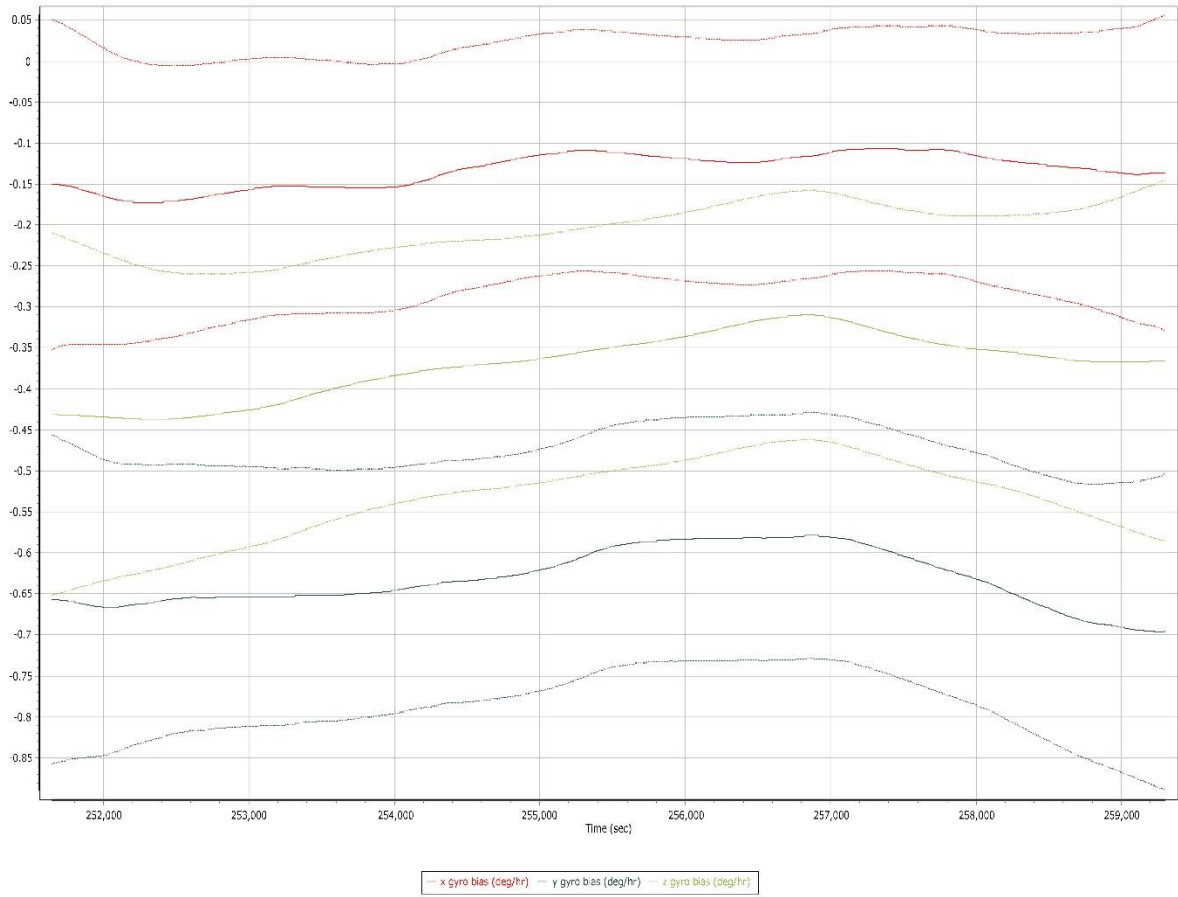


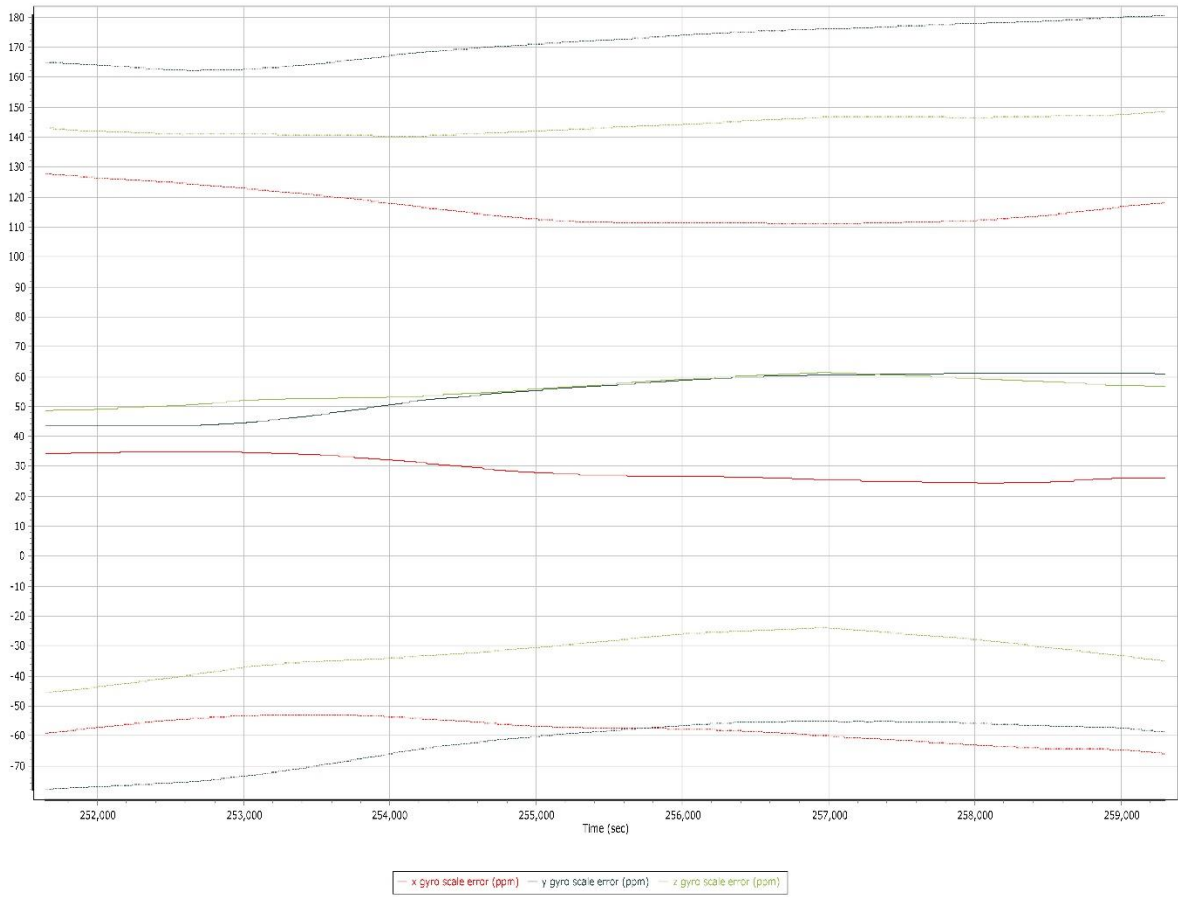




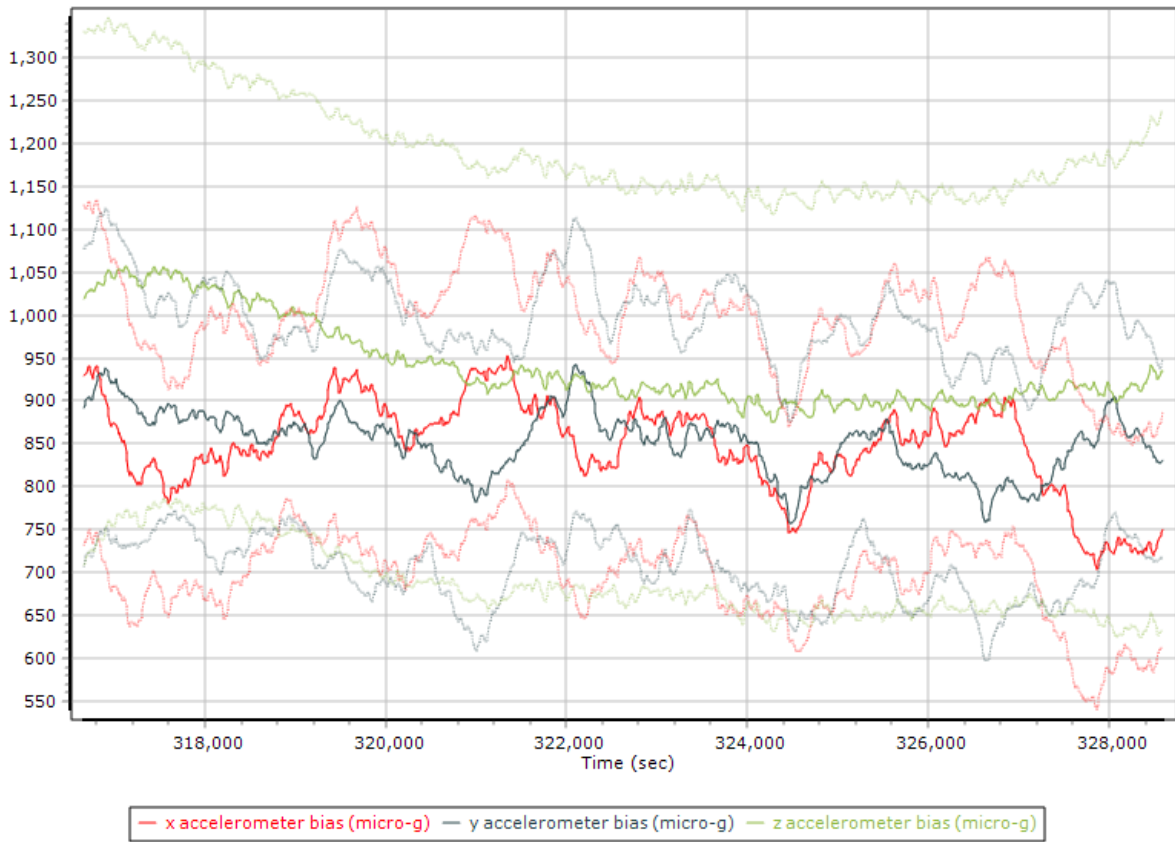


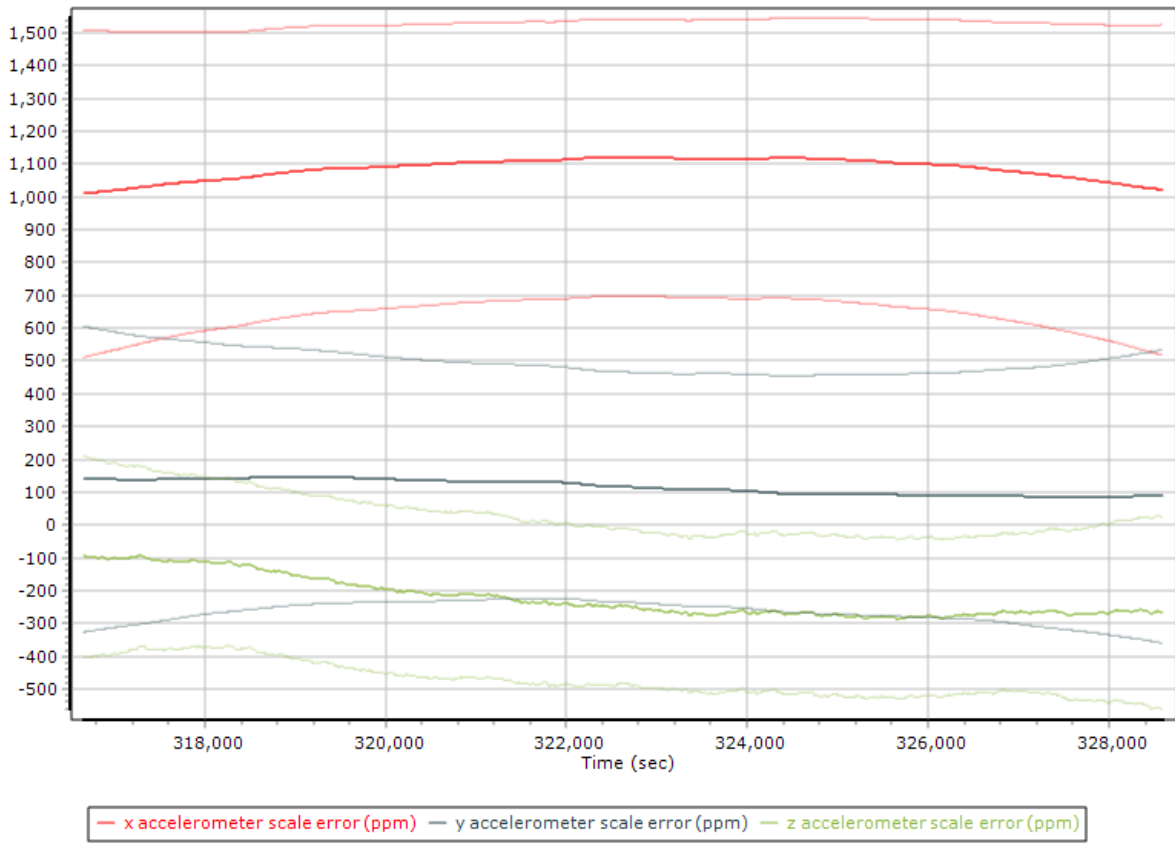


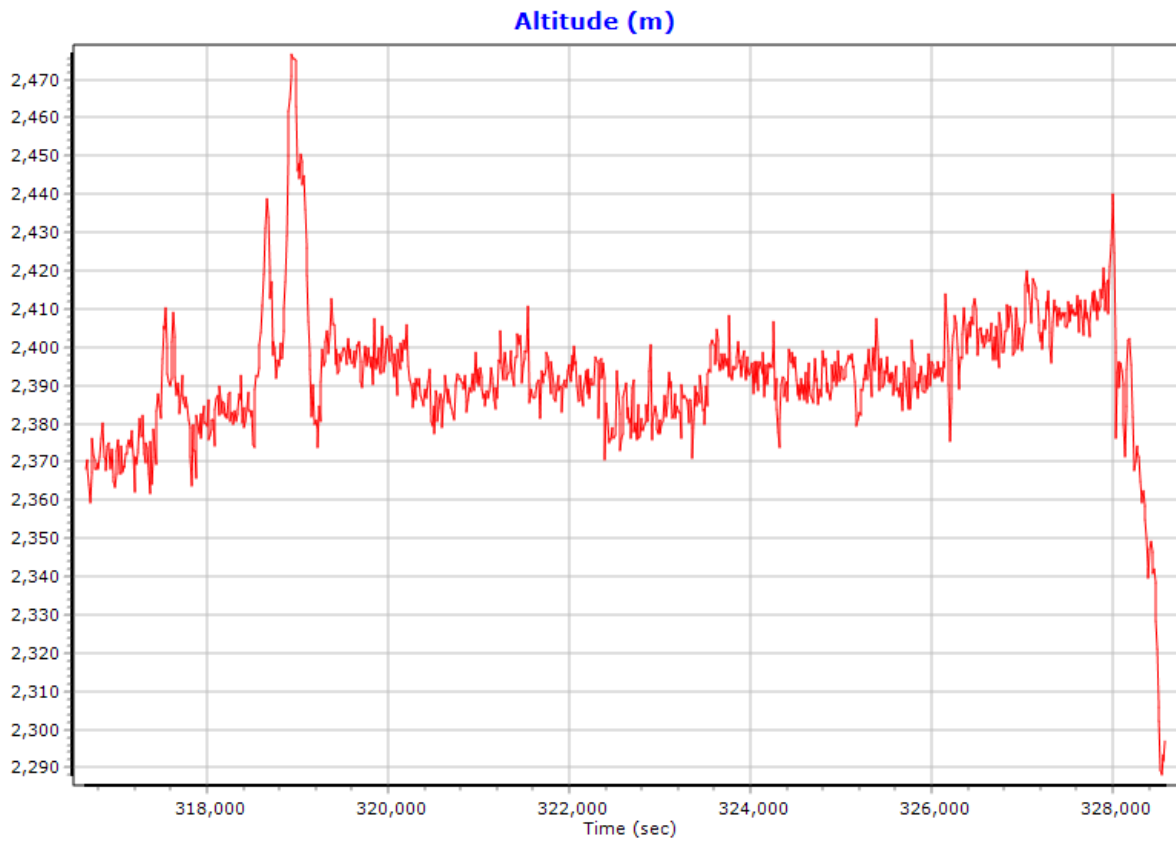


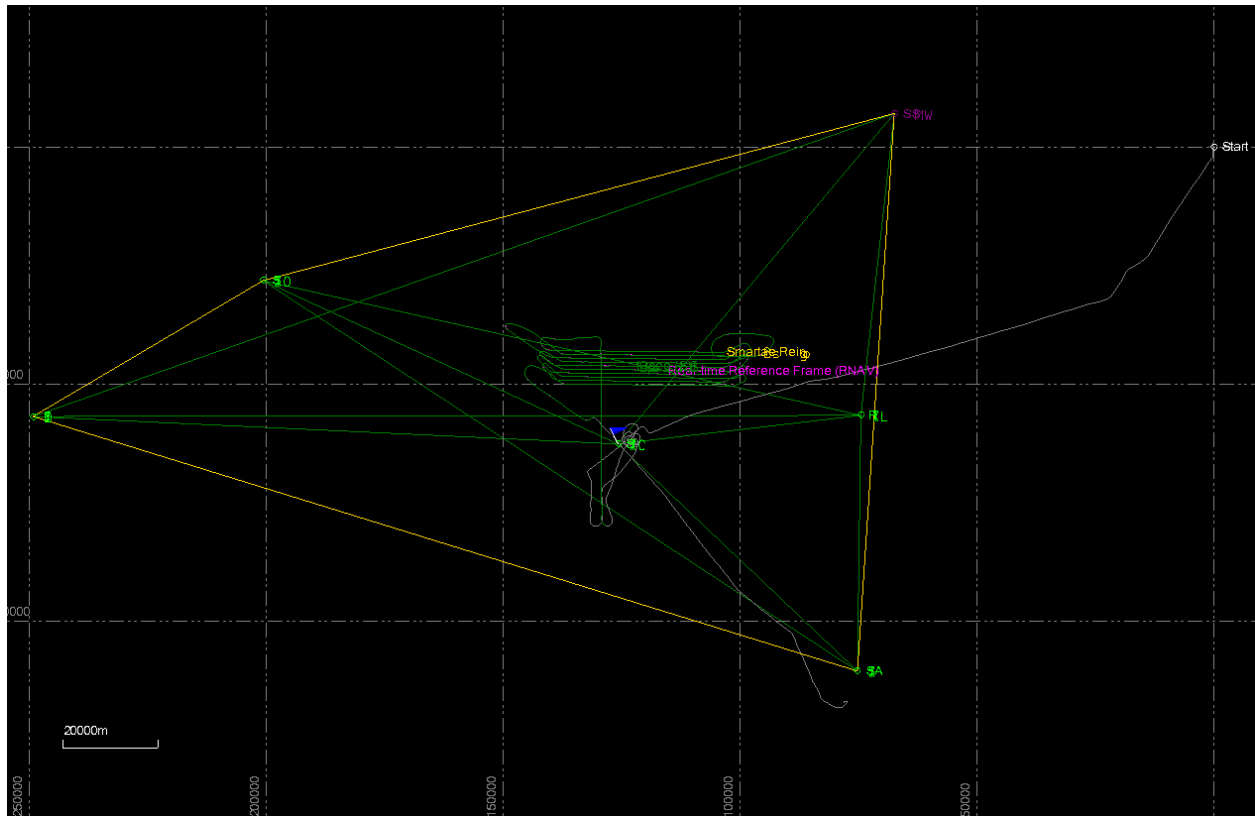
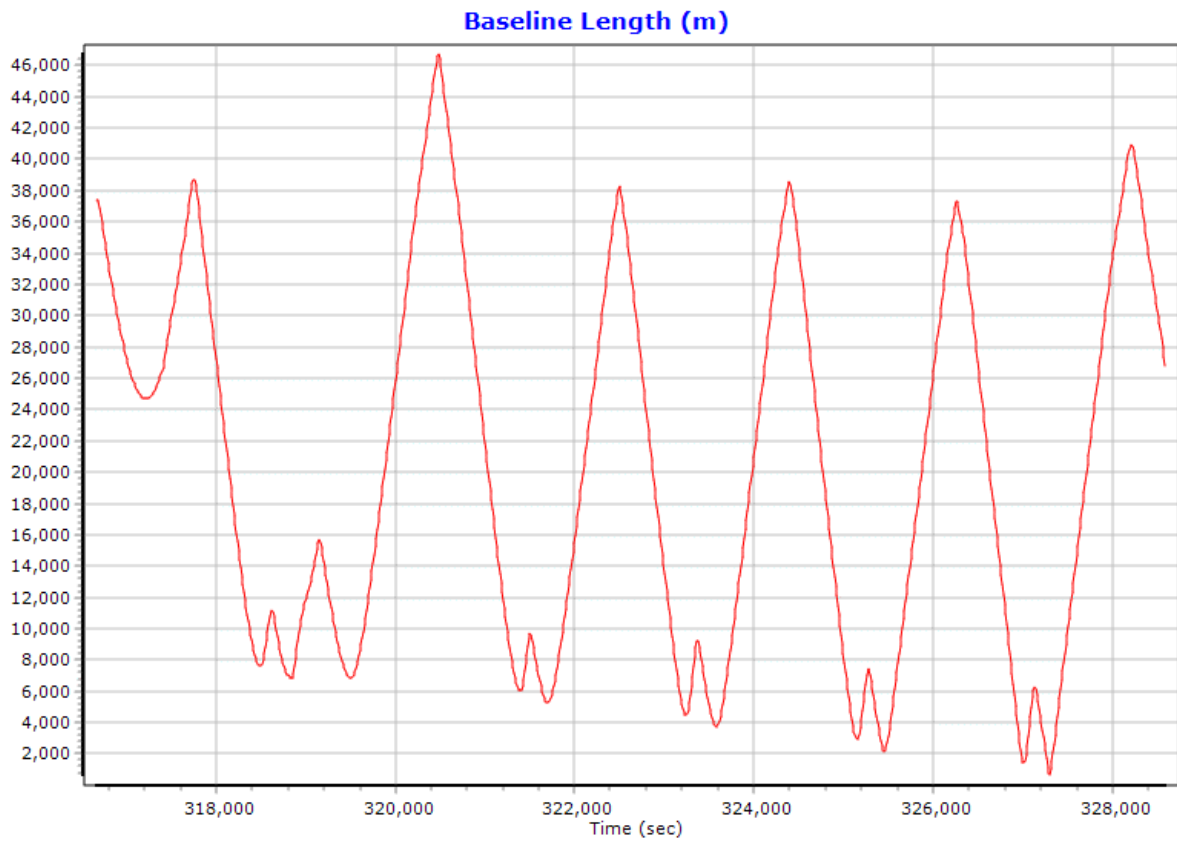


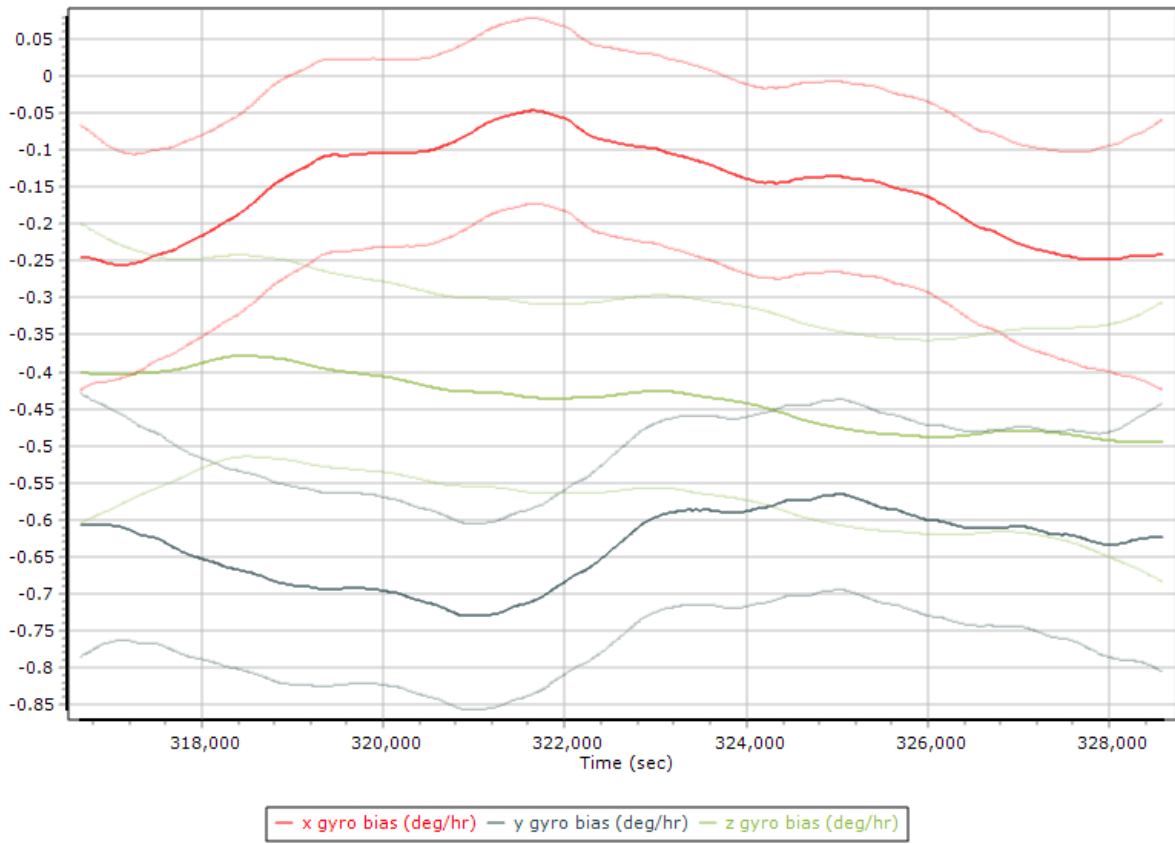
UNB18066A

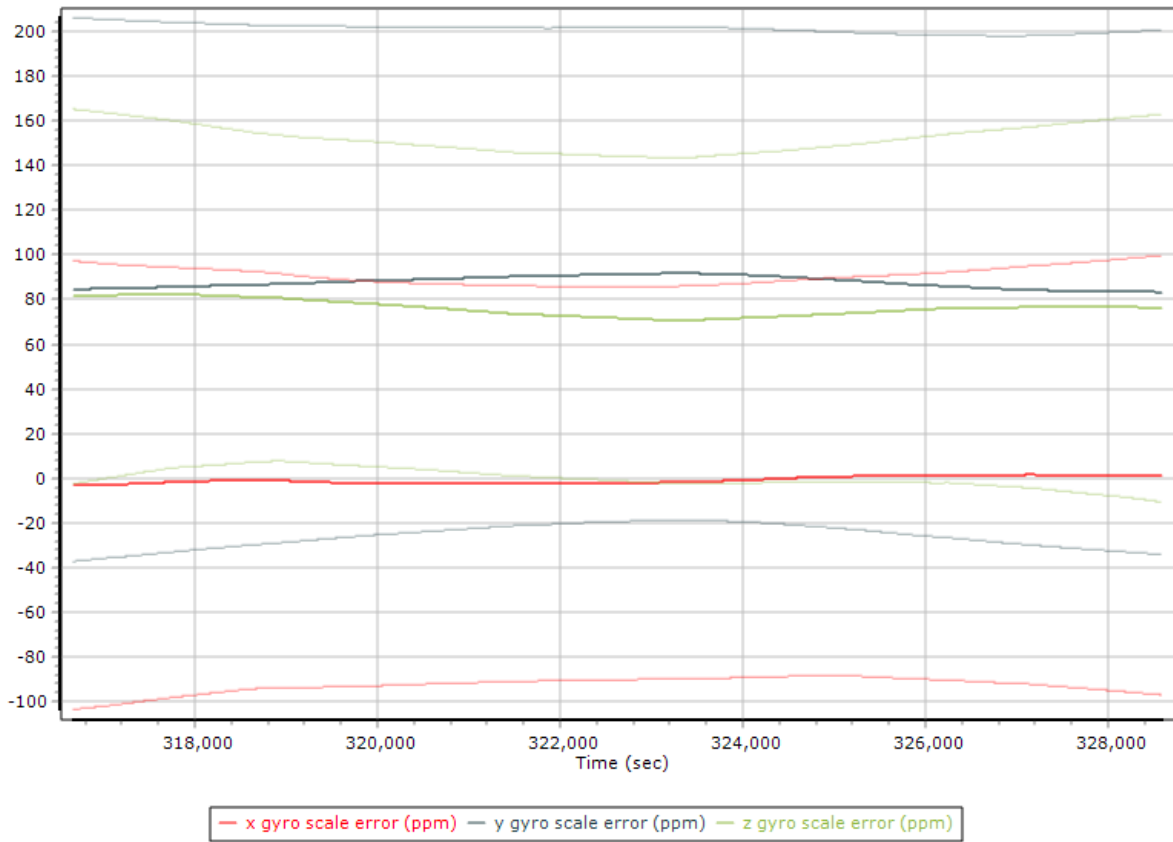












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

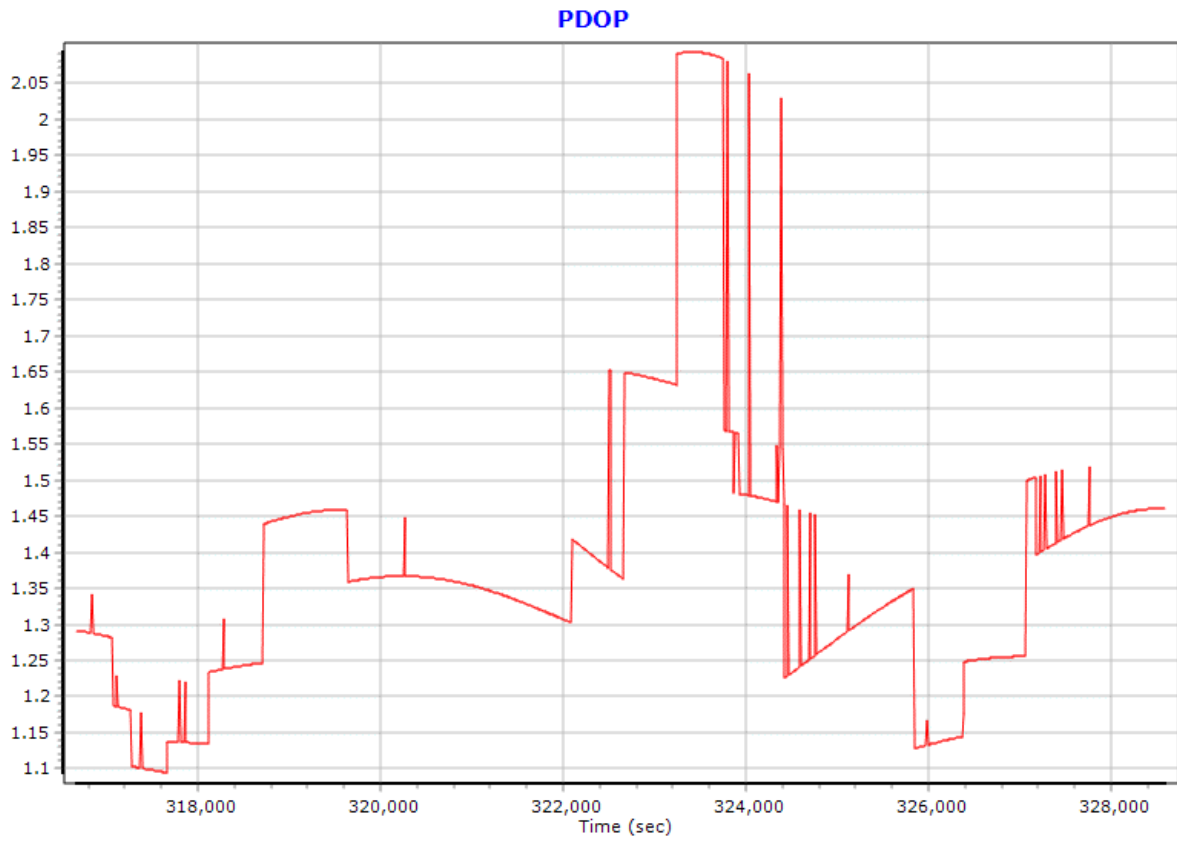
Aircraft to Reference Mounting Angles

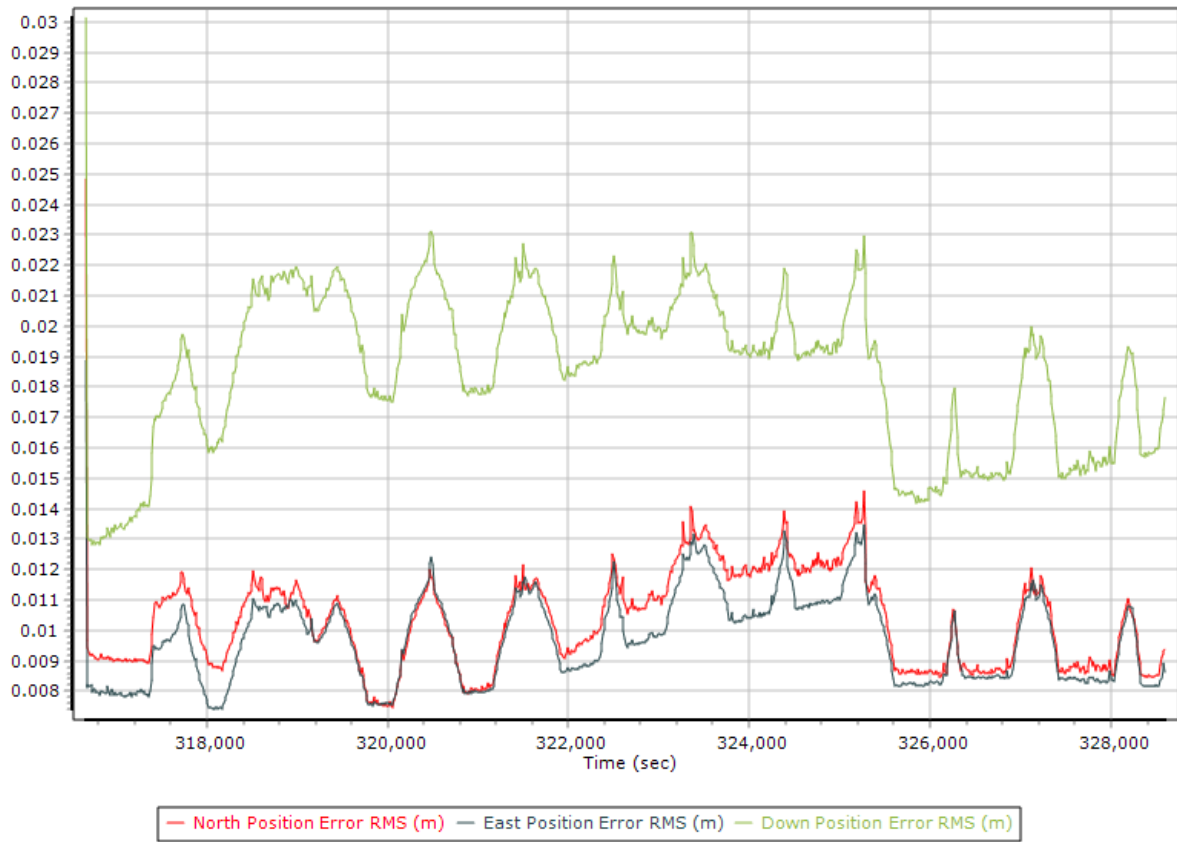
X:

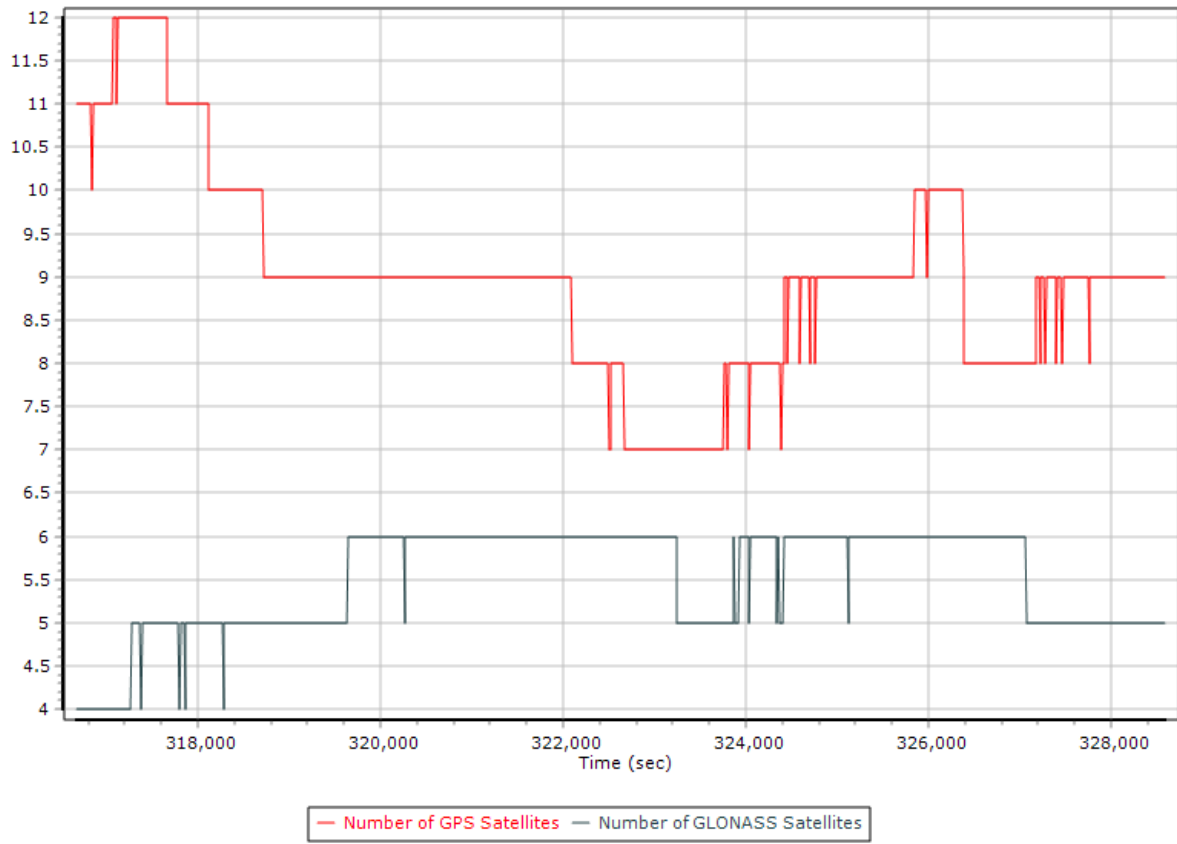
Y:

Z:

OK Cancel









Project Settings

- 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: 316667.146
 End: 328597.562

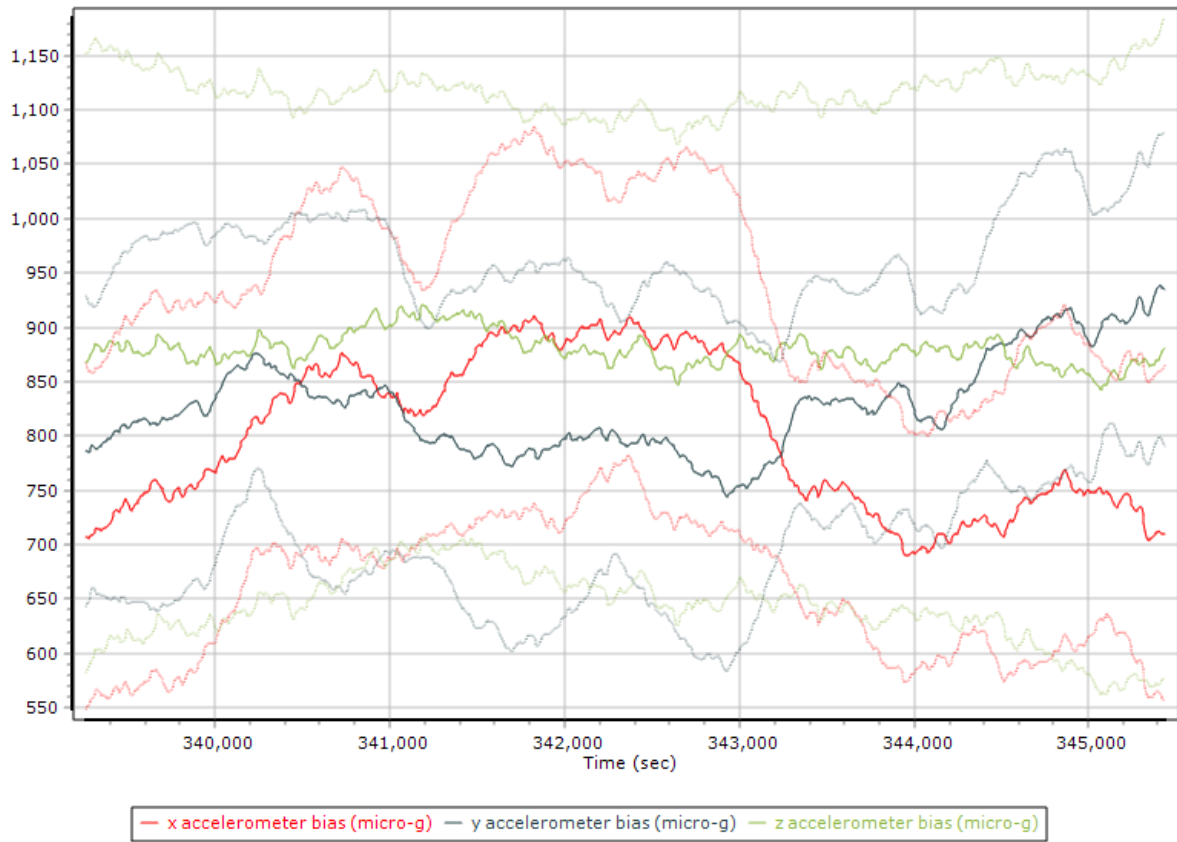
Entire time interval
 Seconds of start week

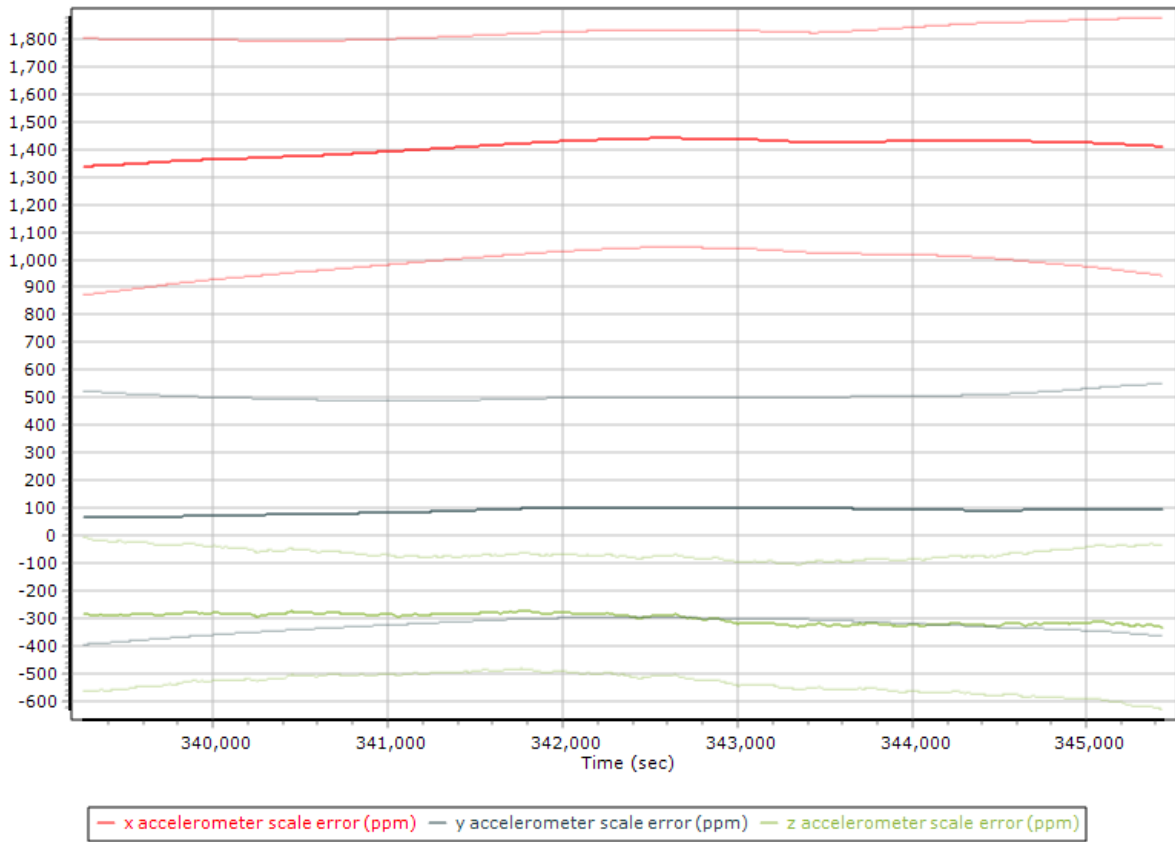
UTC Offset: 18.000

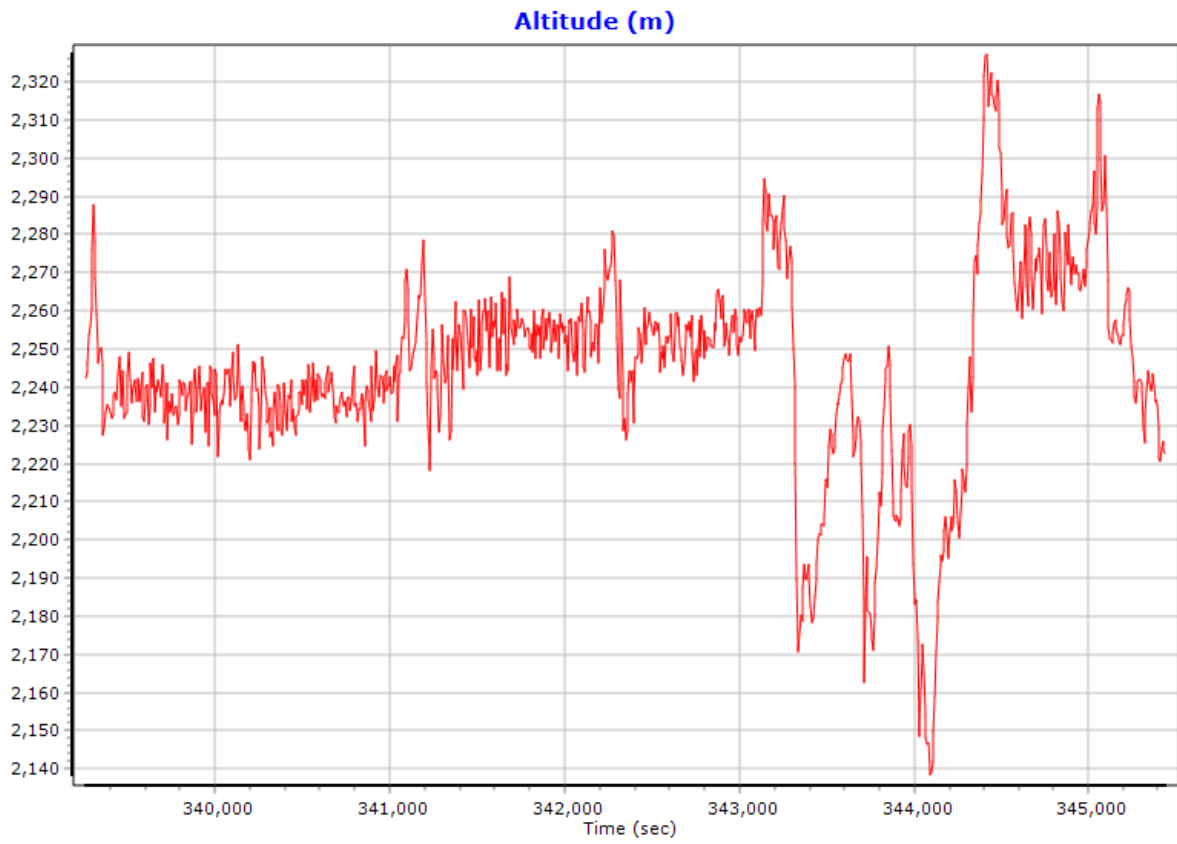
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

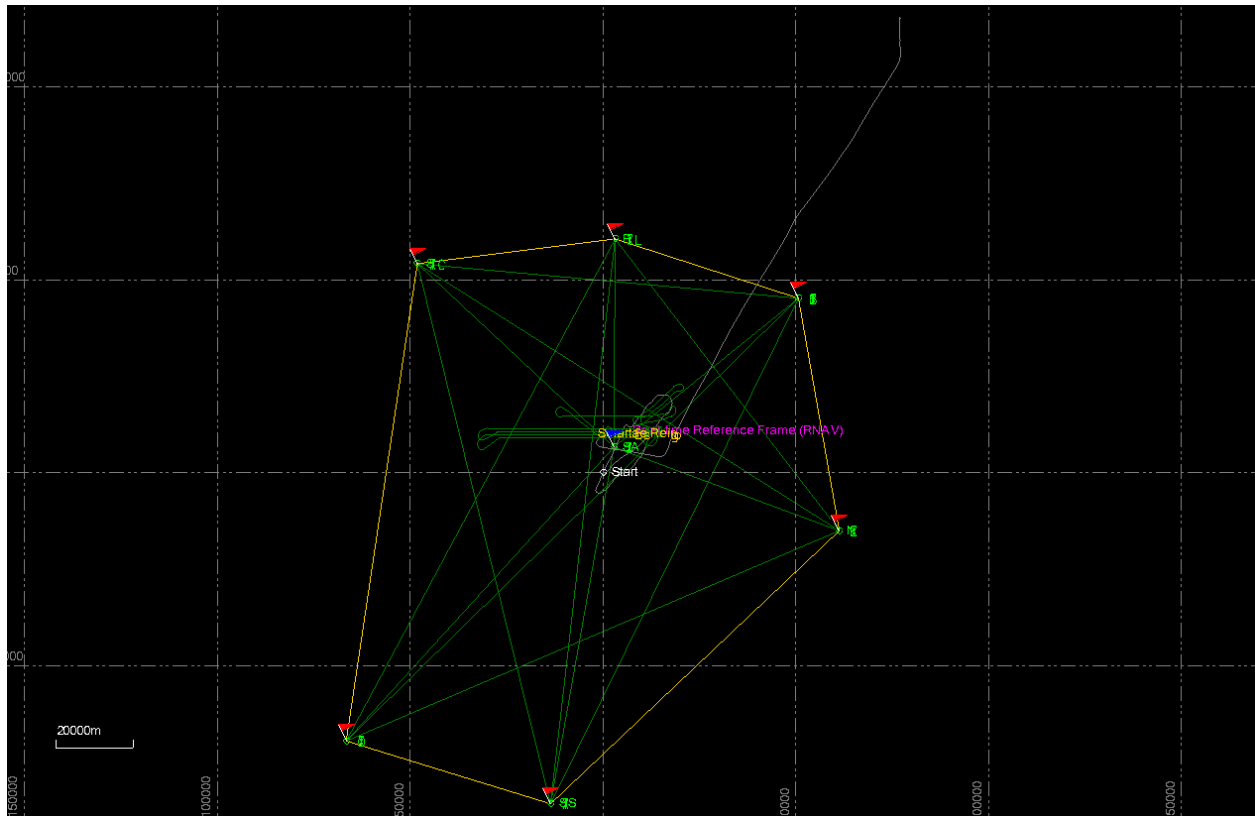
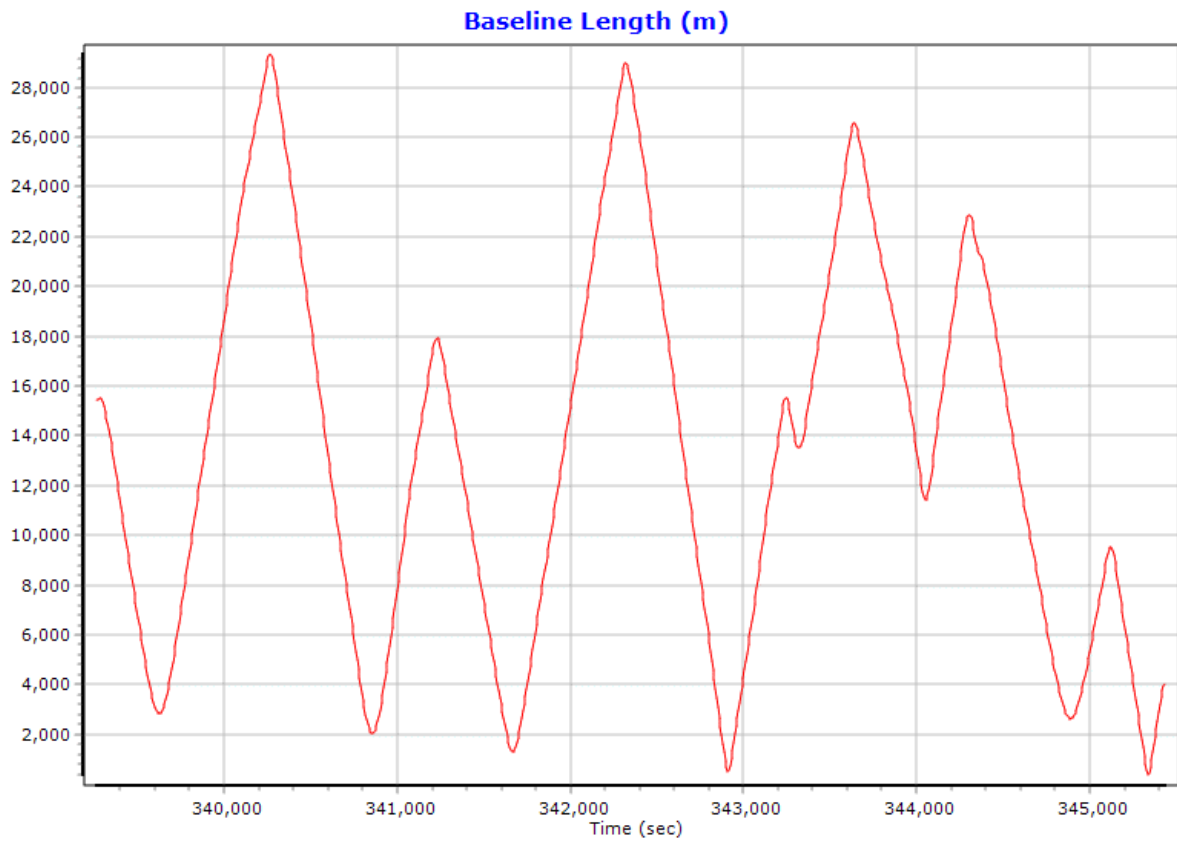
OK Cancel

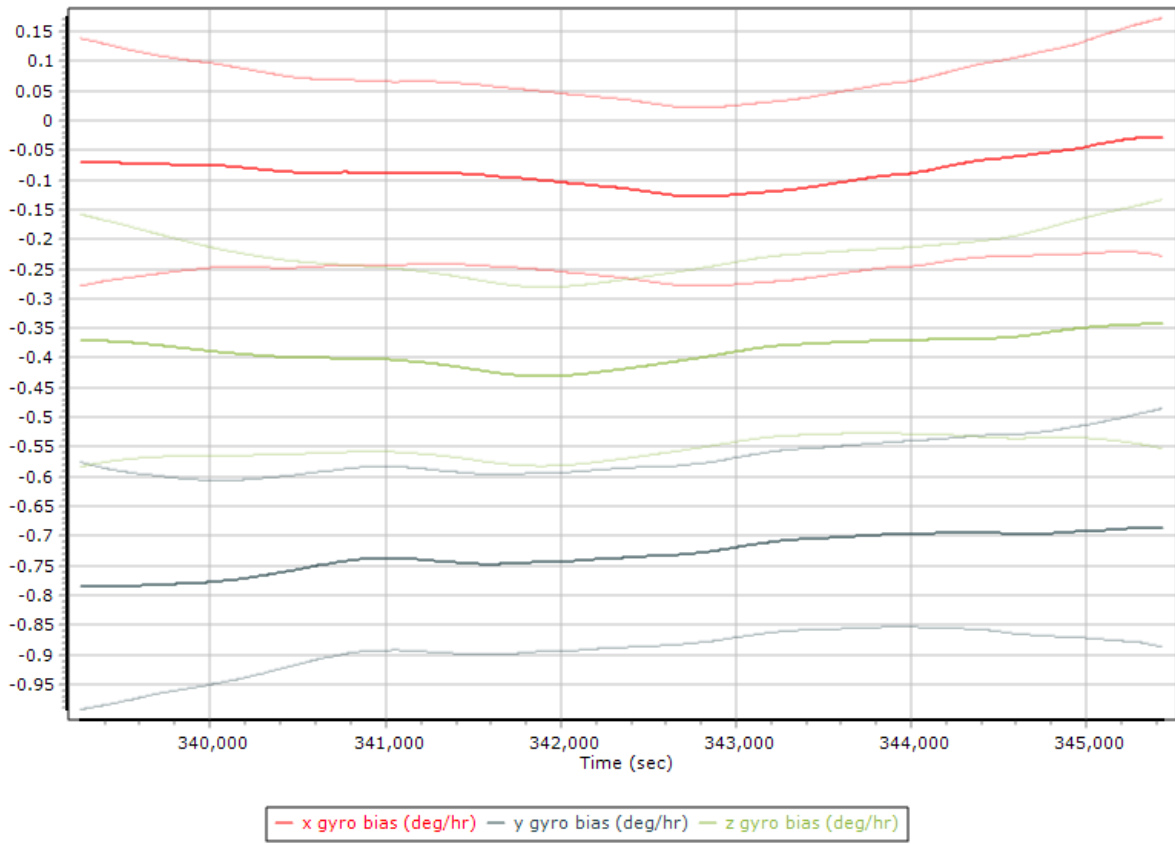
UNB18066B

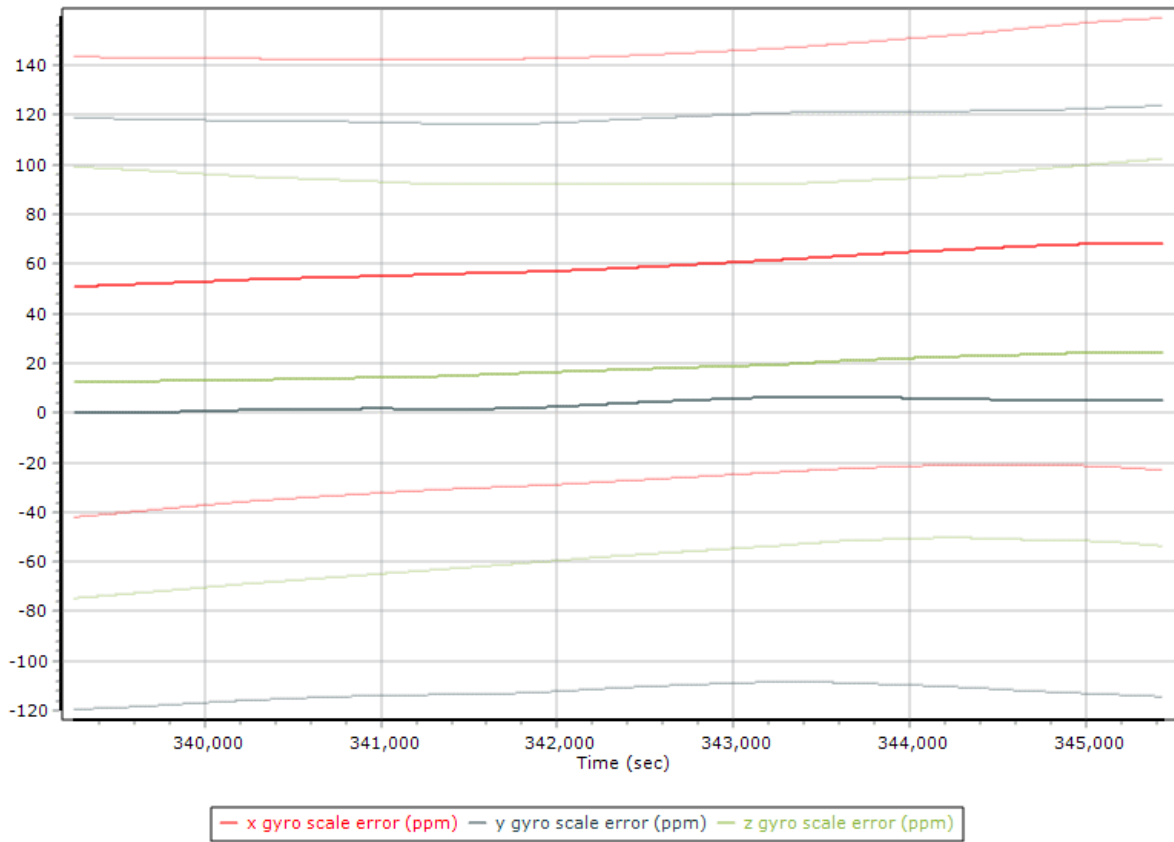












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

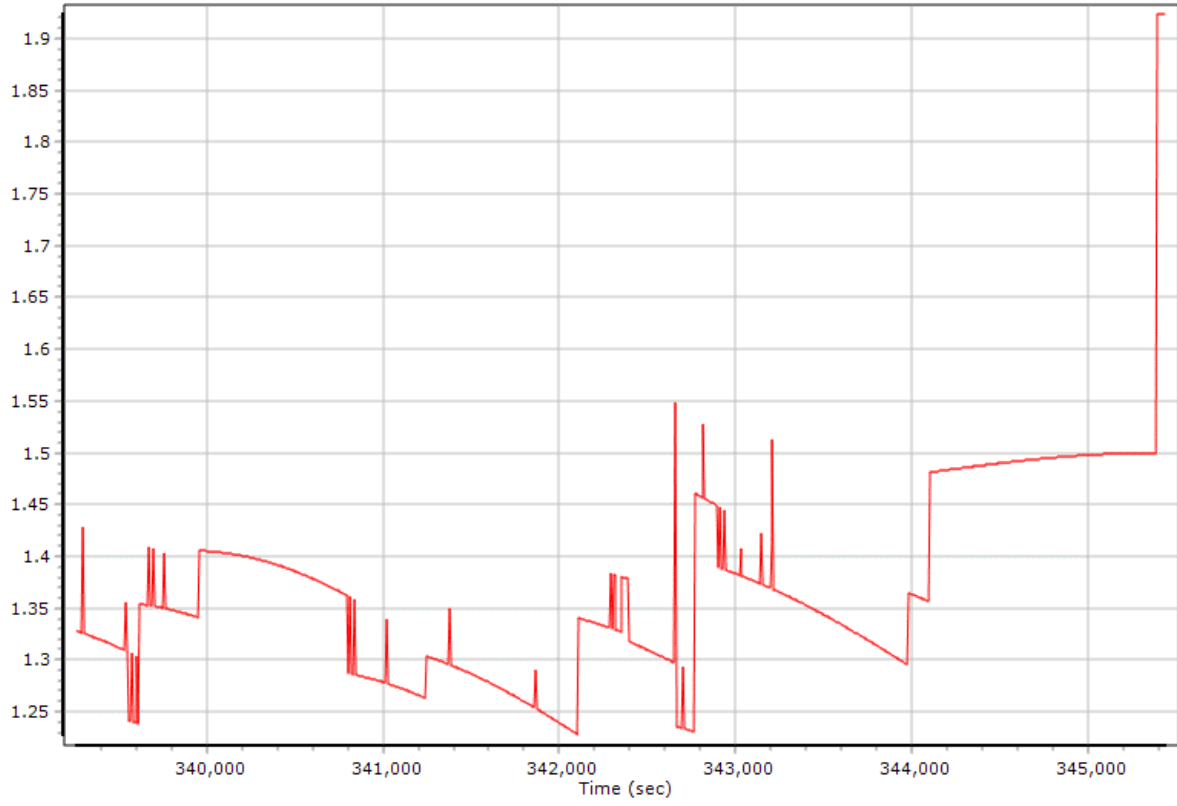
Aircraft to Reference Mounting Angles

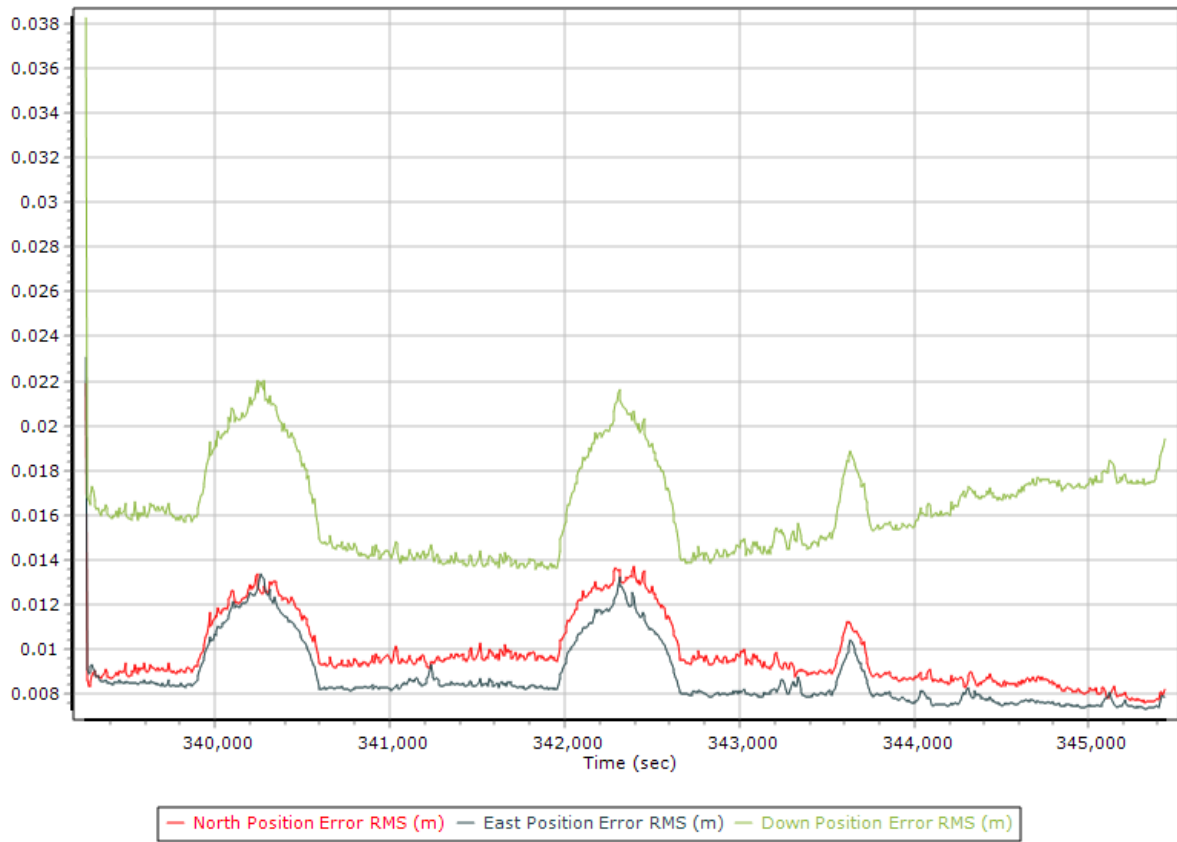
X:

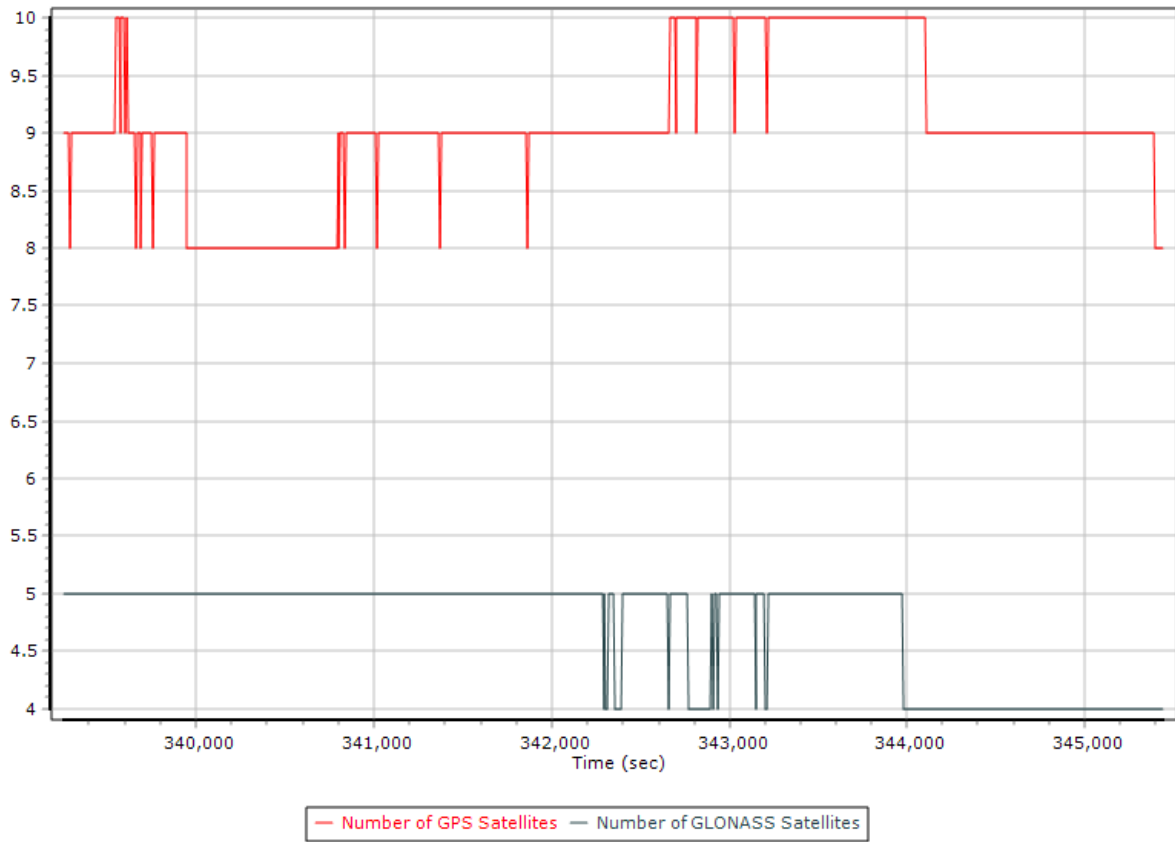
Y:

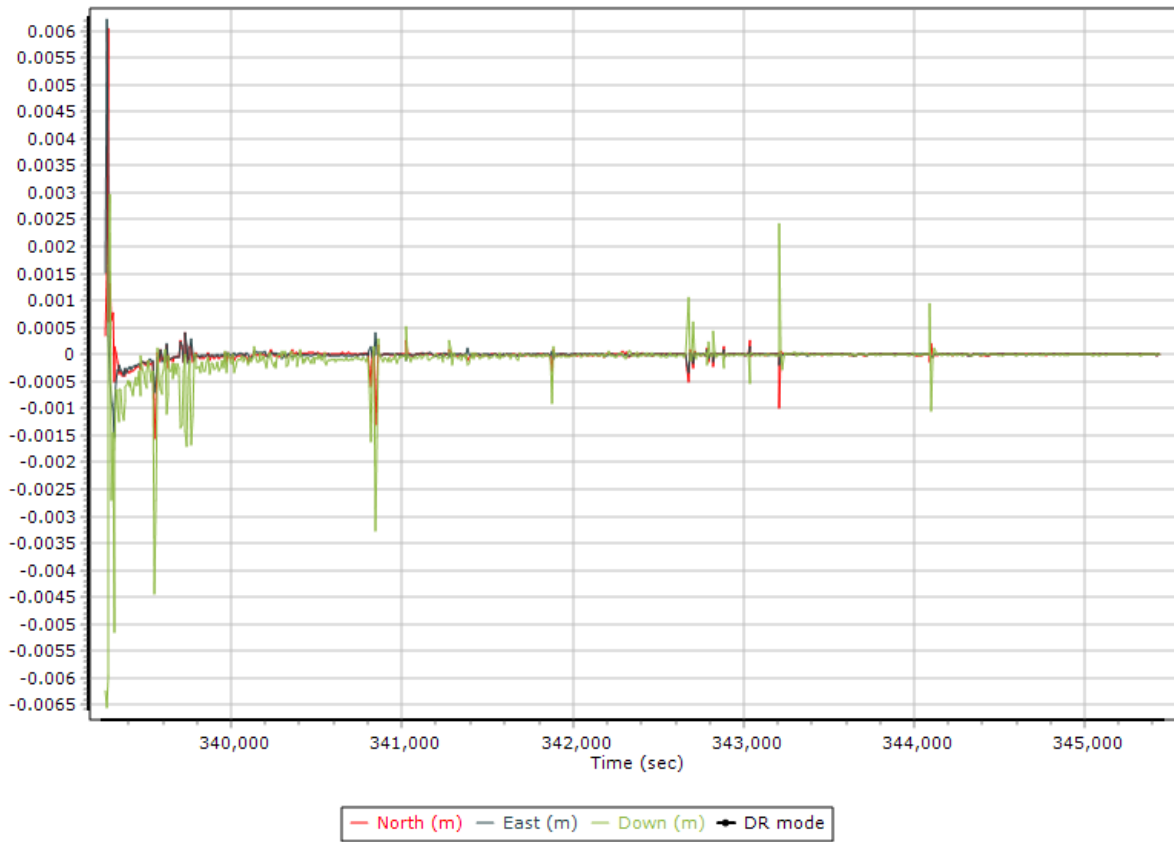
Z:

PDOP









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: 339258.805
End: 345445.026

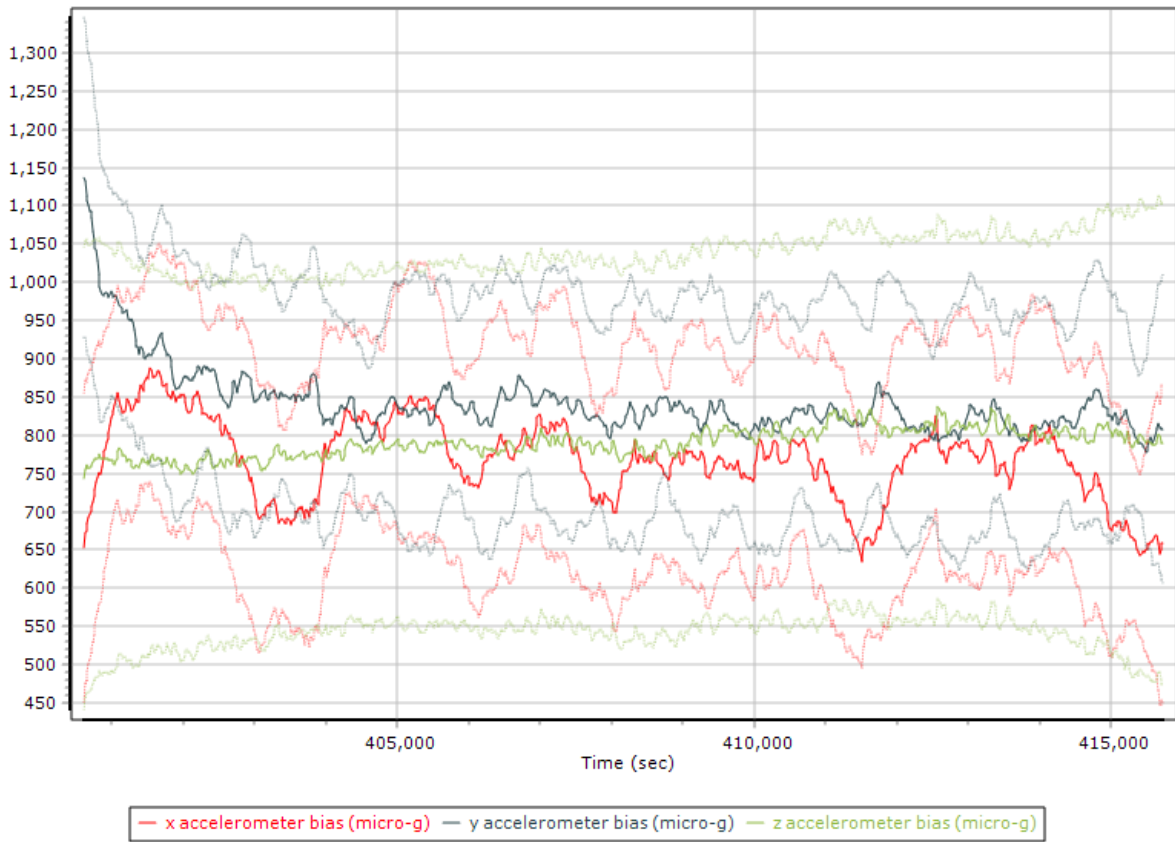
Entire time interval
 Seconds of start week

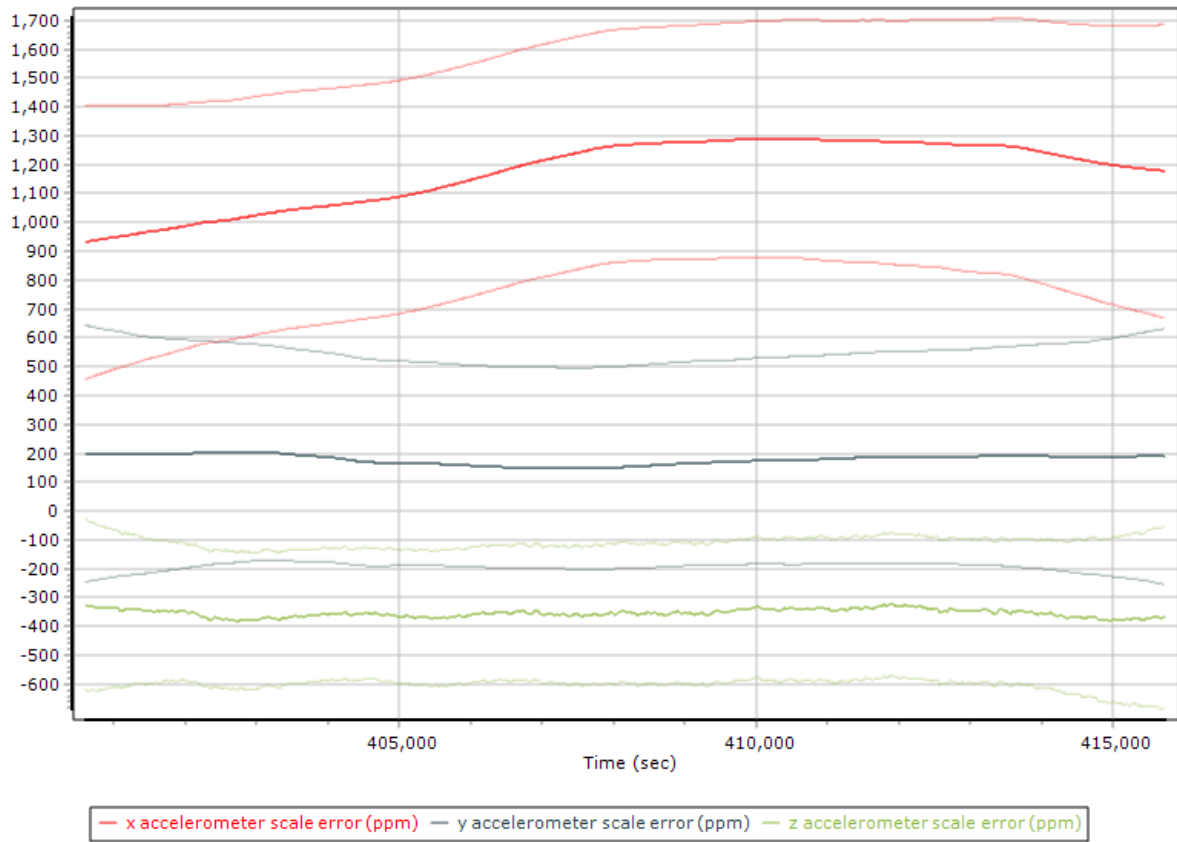
UTC Offset: 18.000

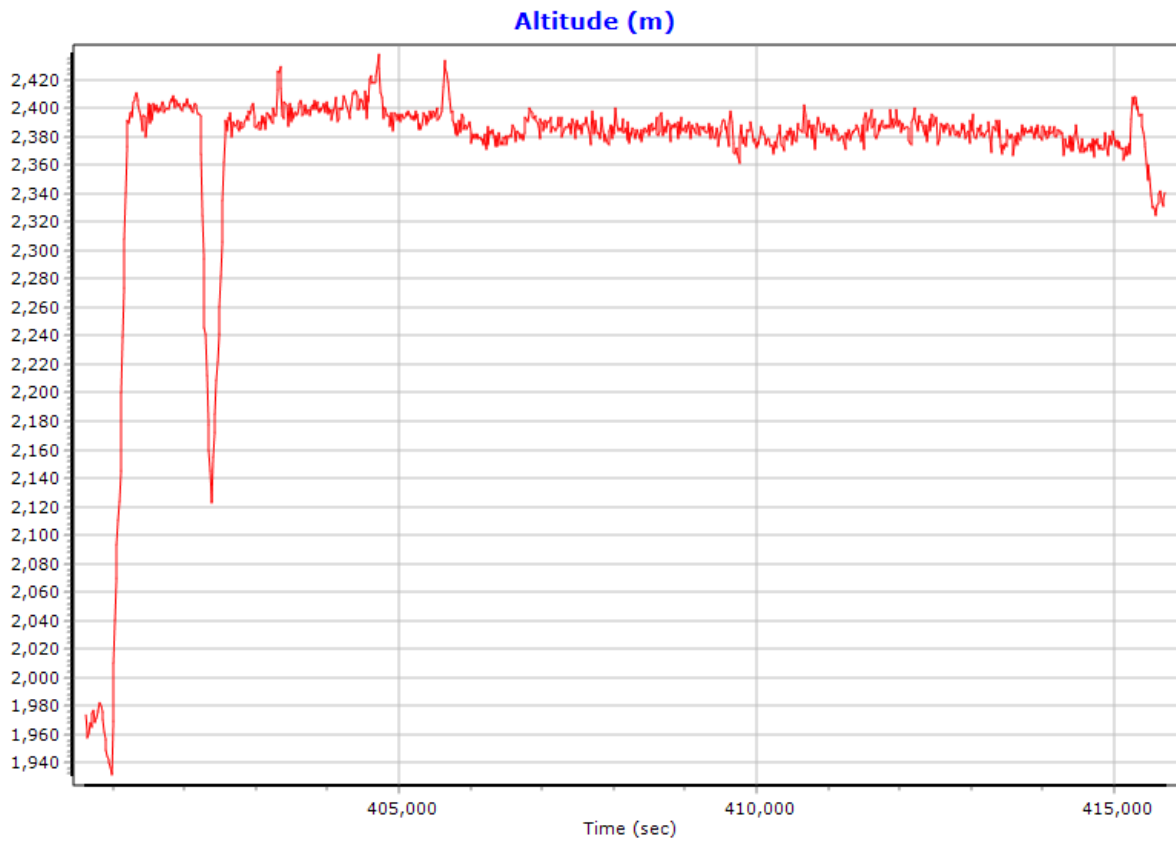
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

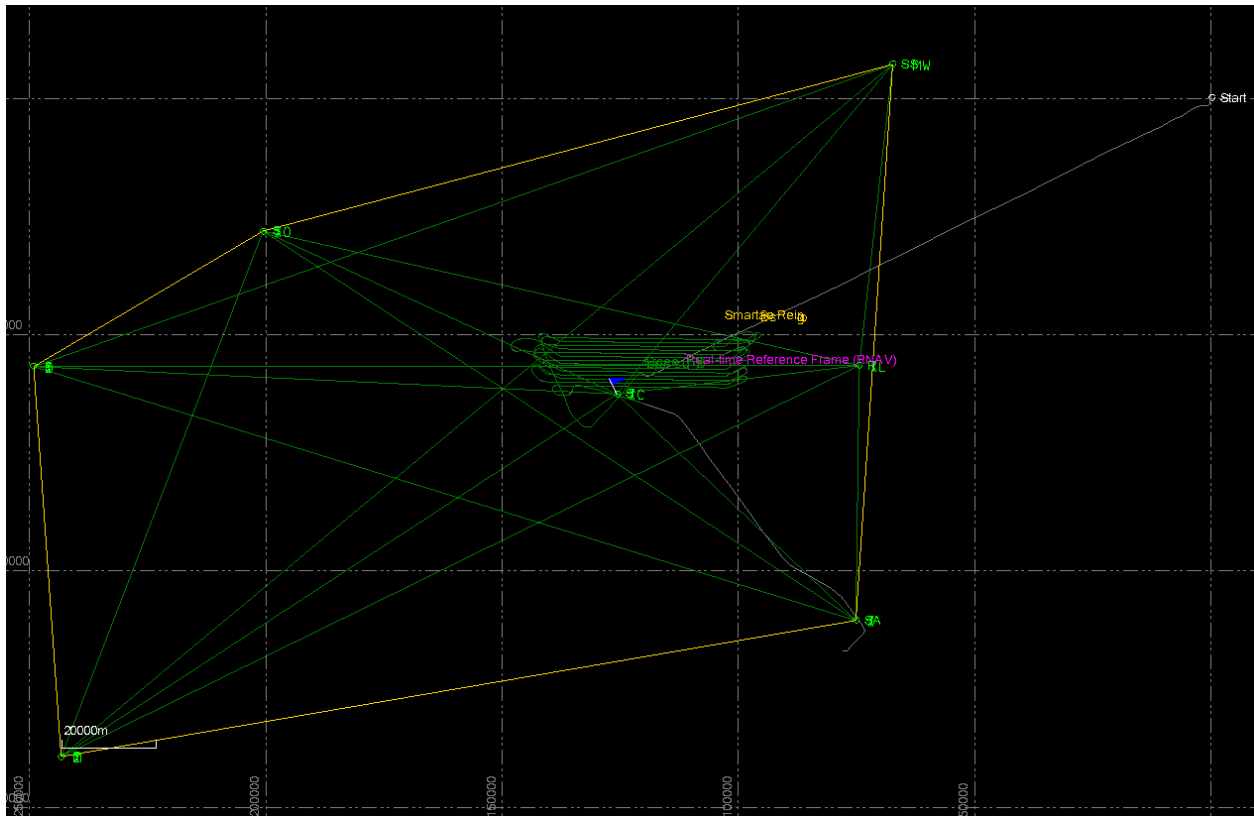
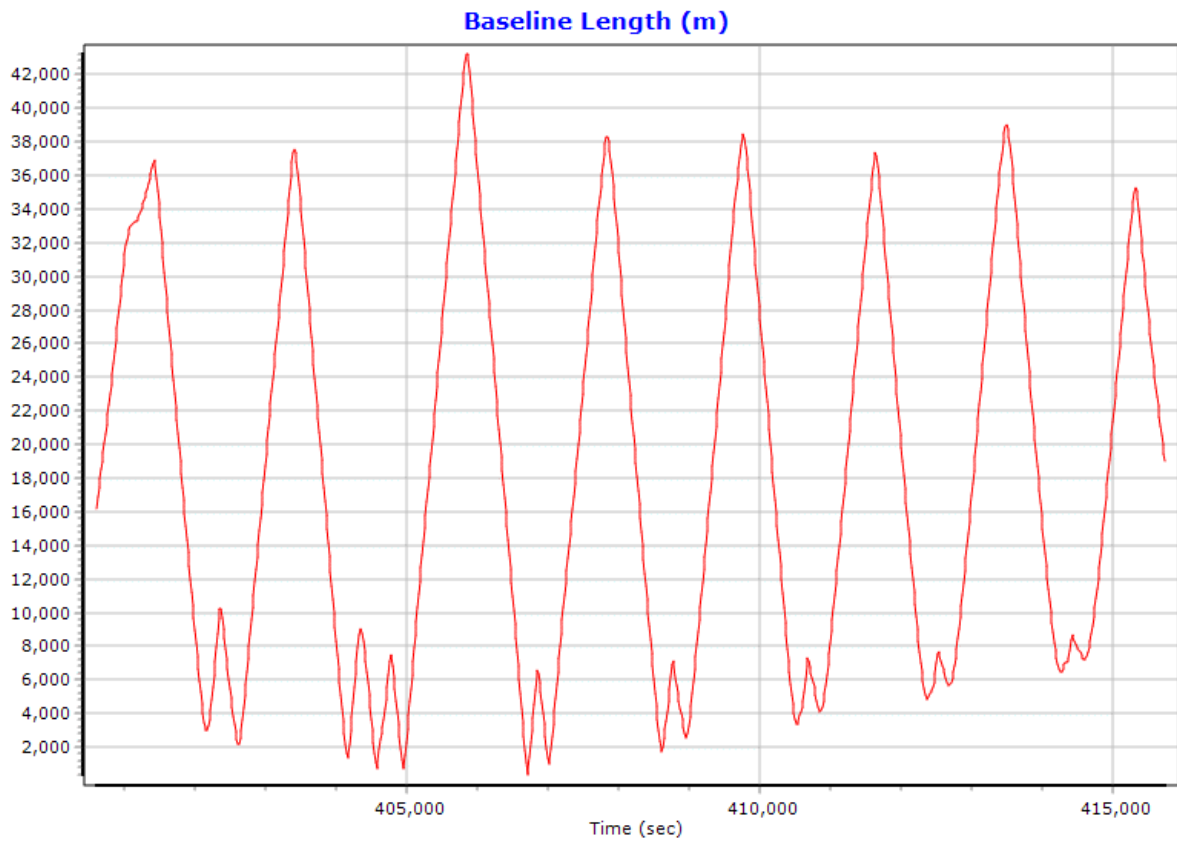
OK Cancel

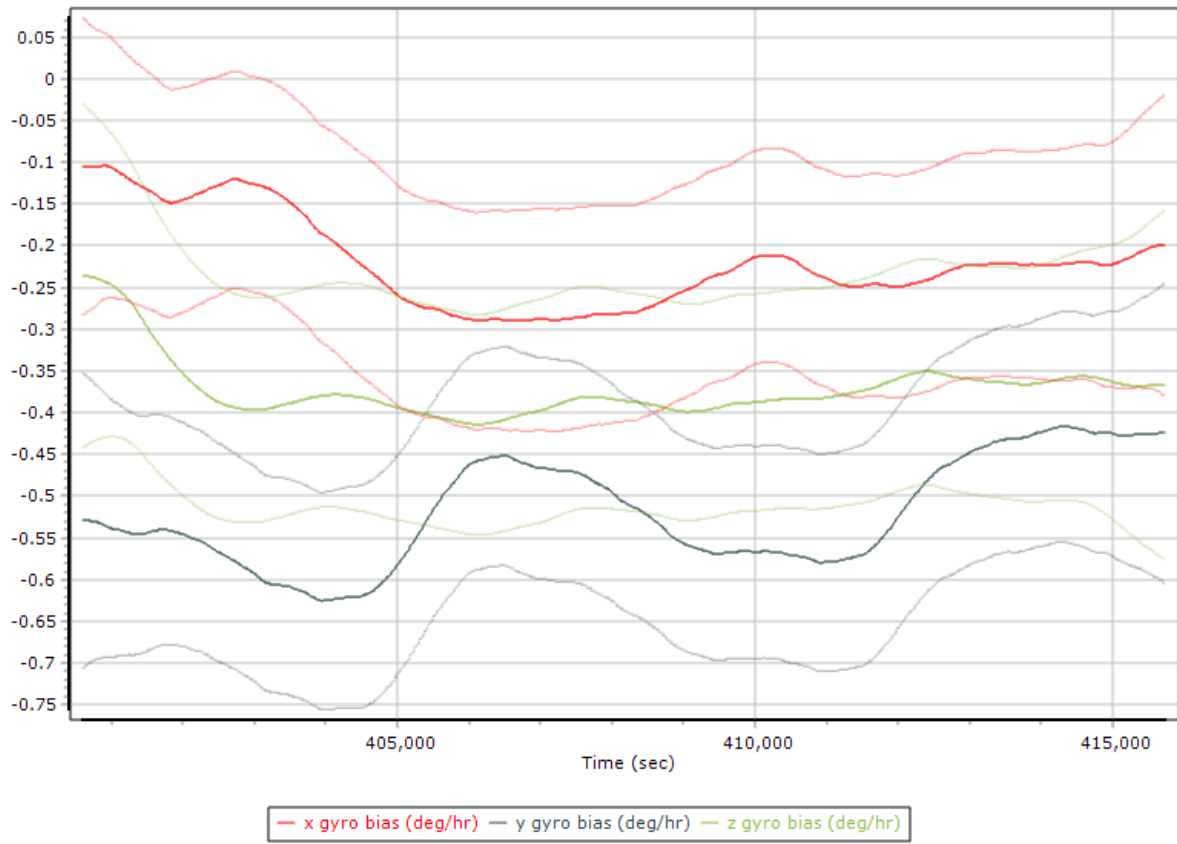
UNB18067A

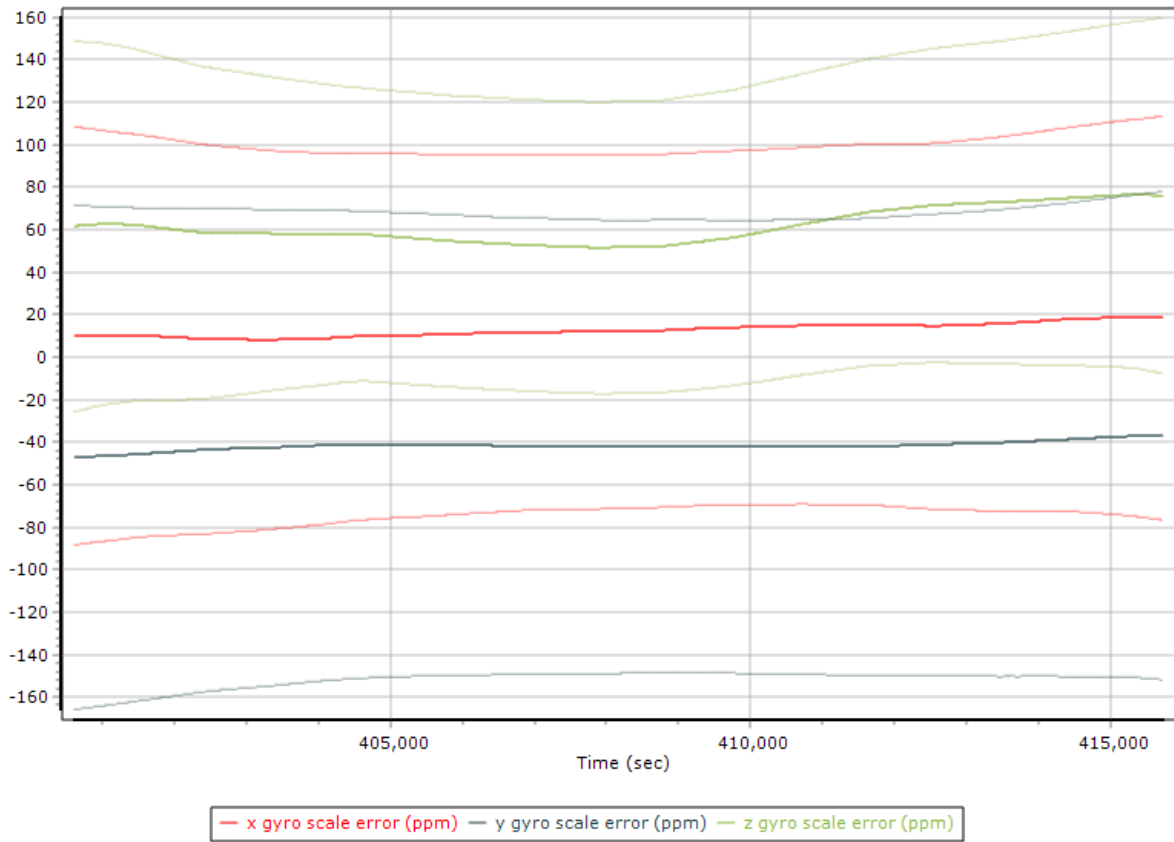












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

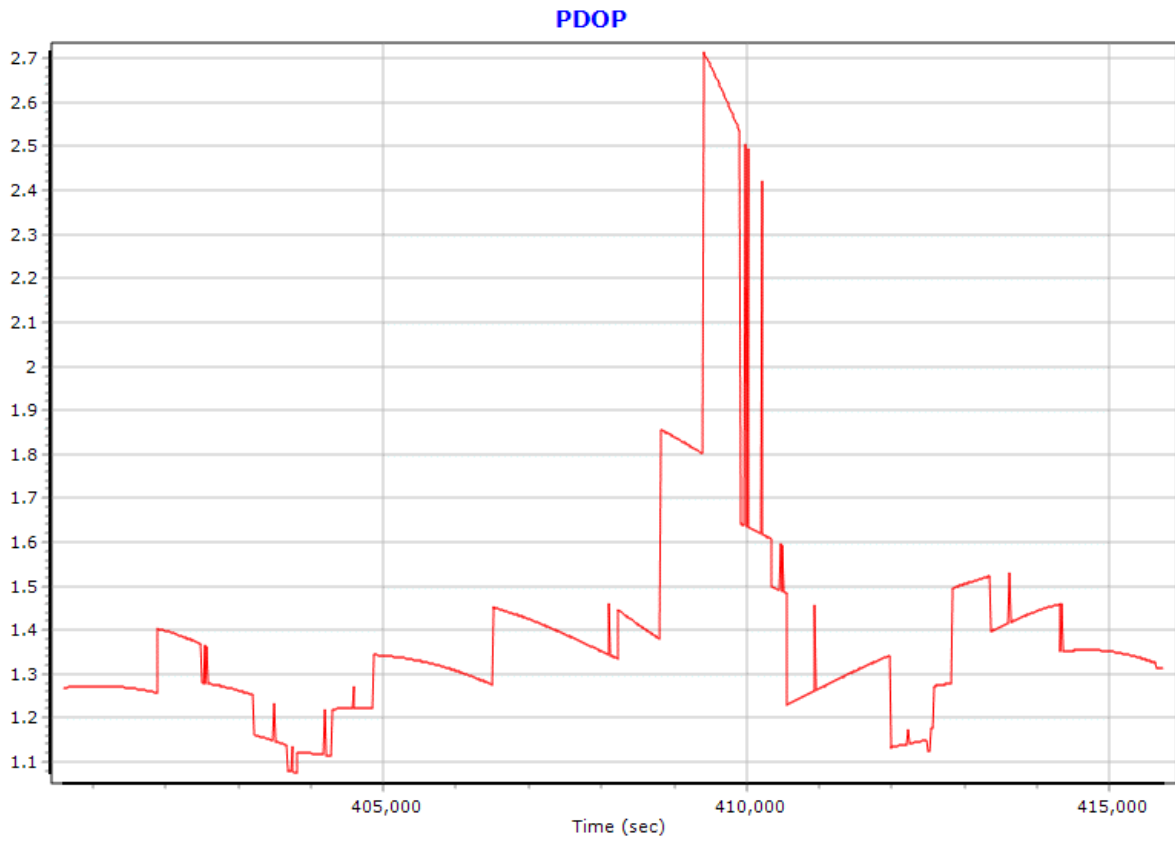
Aircraft to Reference Mounting Angles

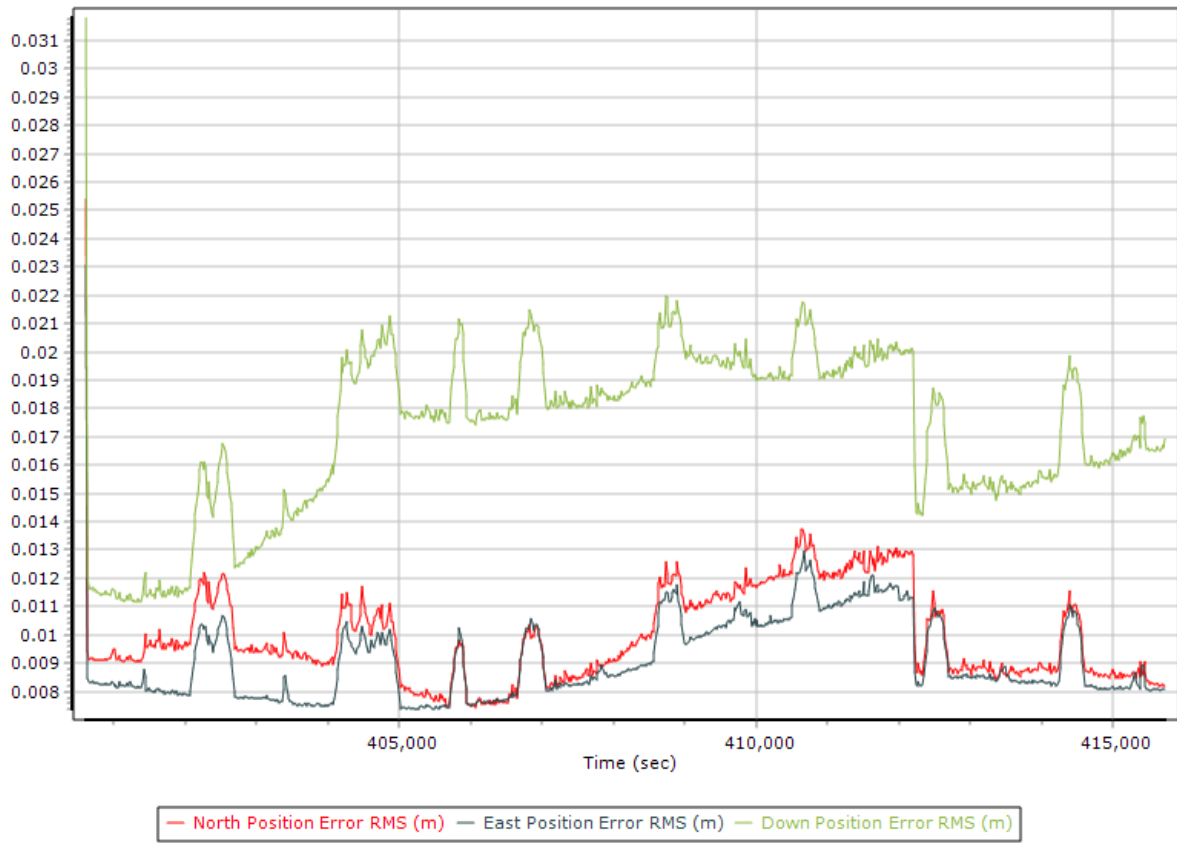
X:

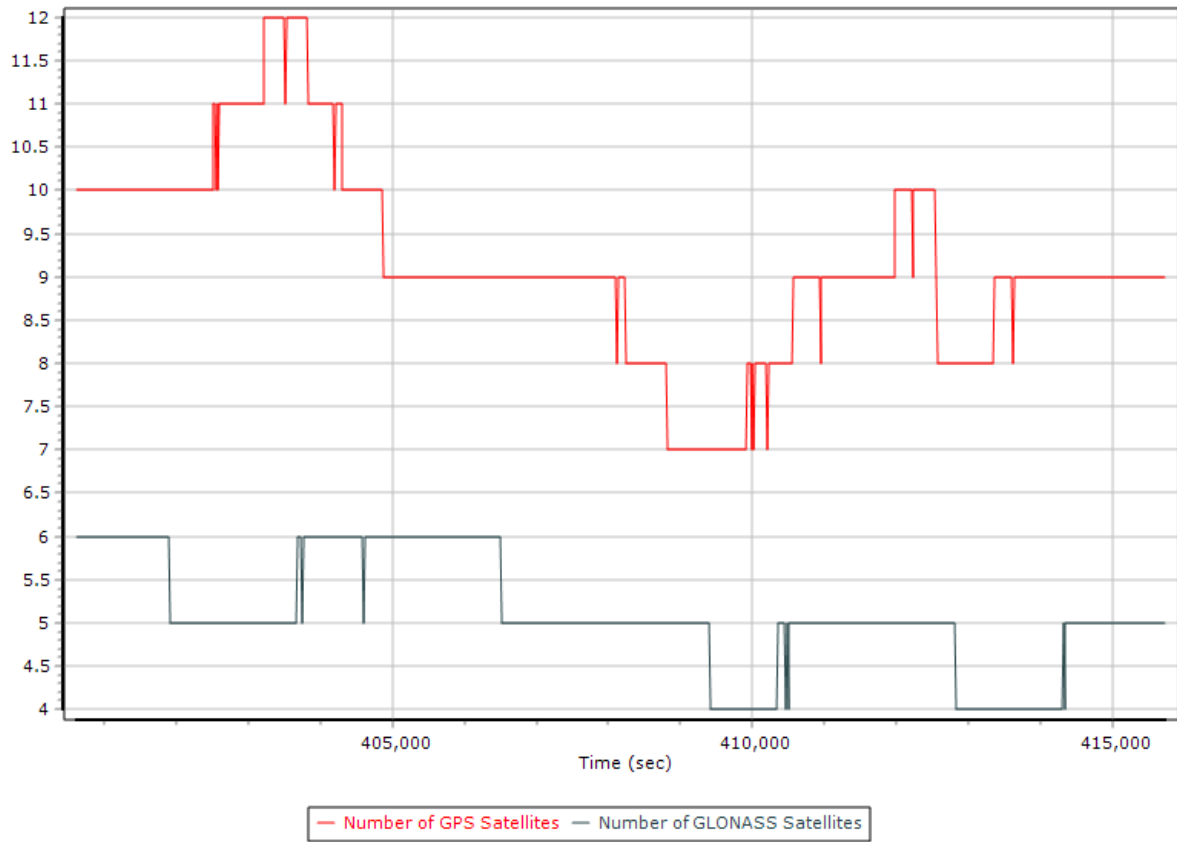
Y:

Z:

OK Cancel









Project Settings ✕

- 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:

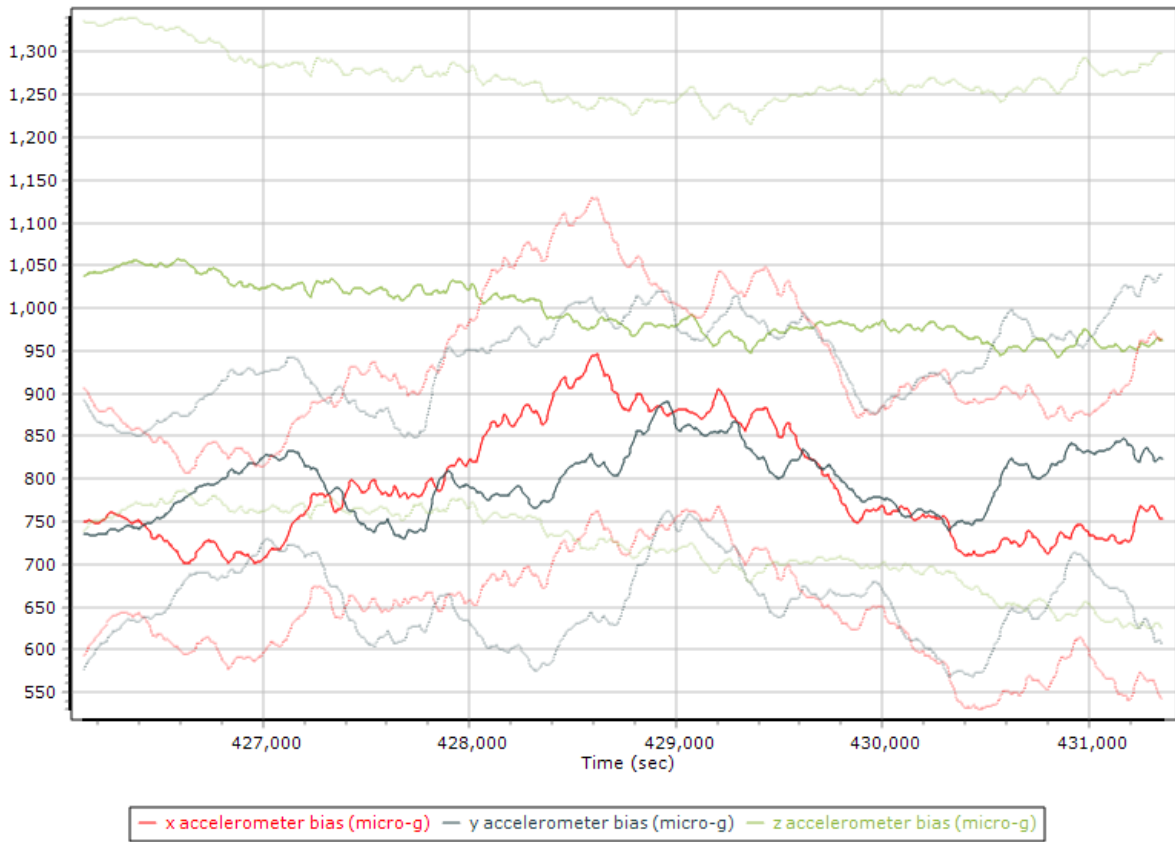
End:

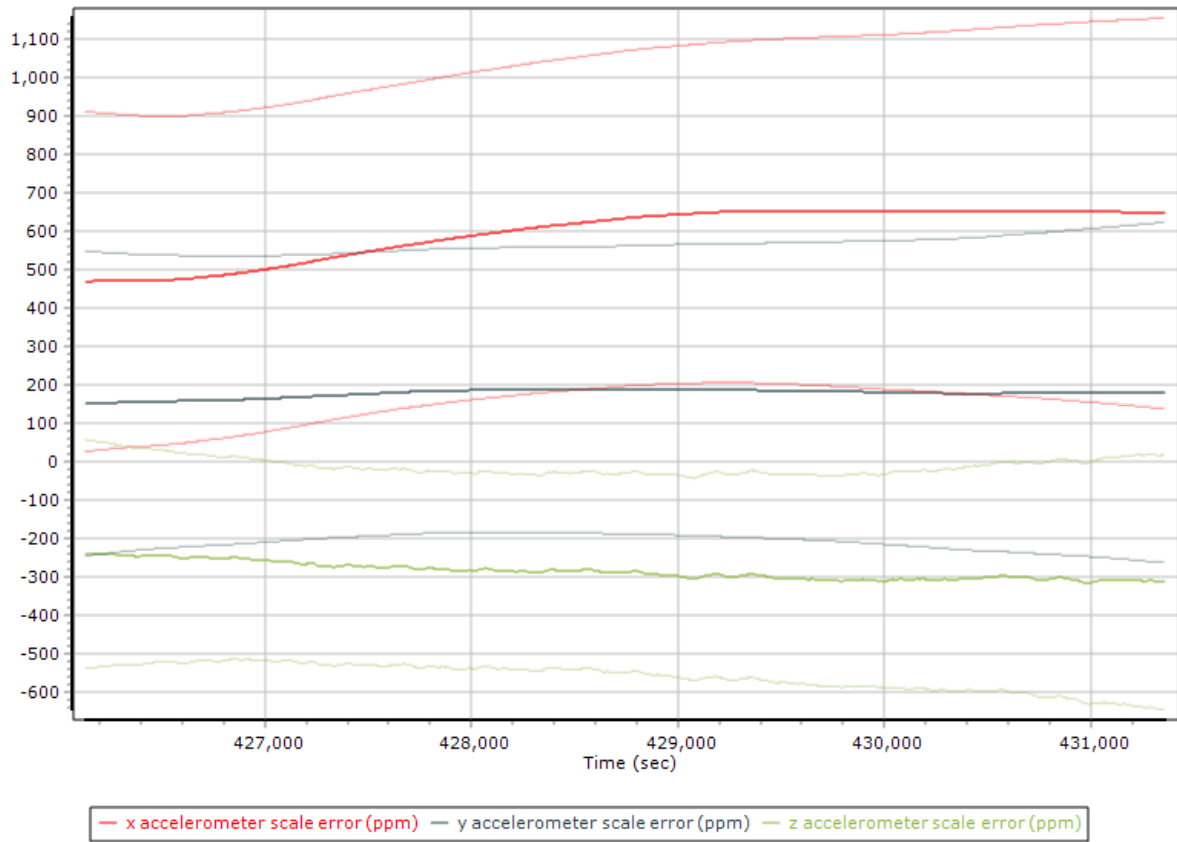
Entire time interval
 Seconds of start week

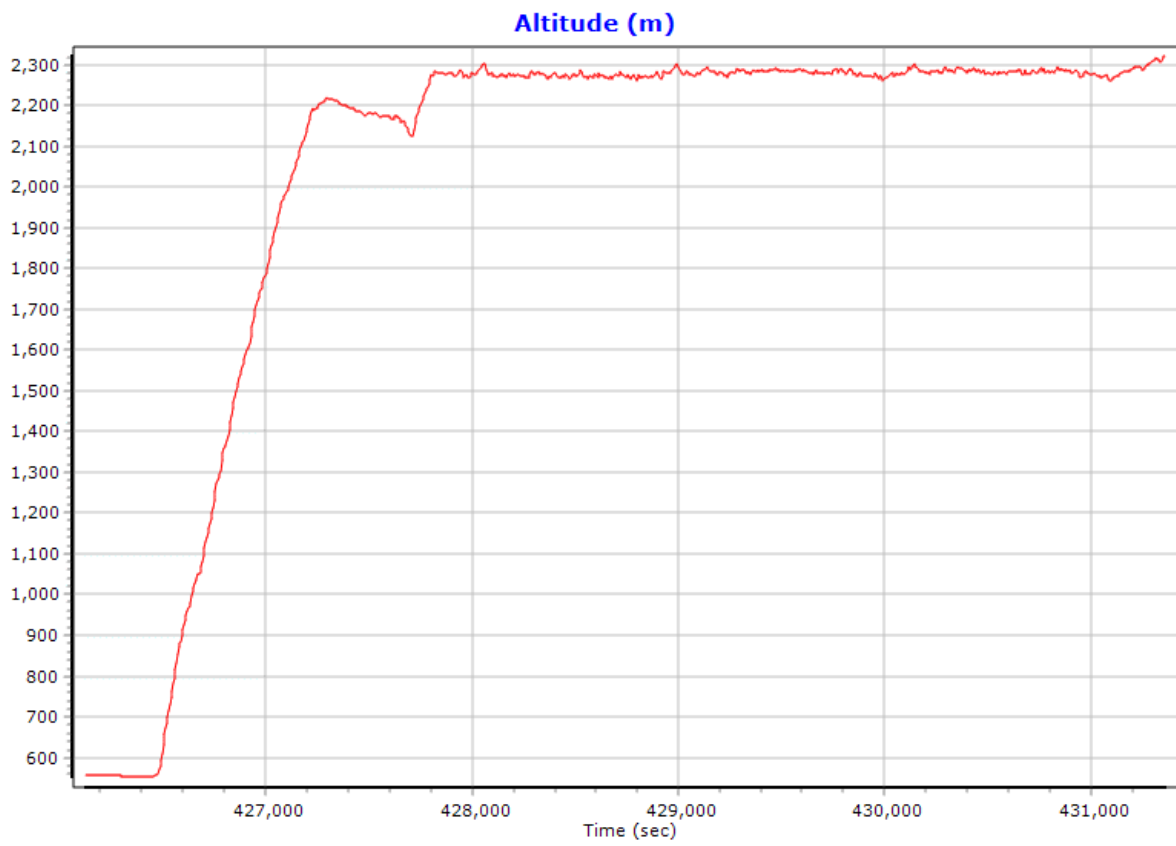
UTC Offset:

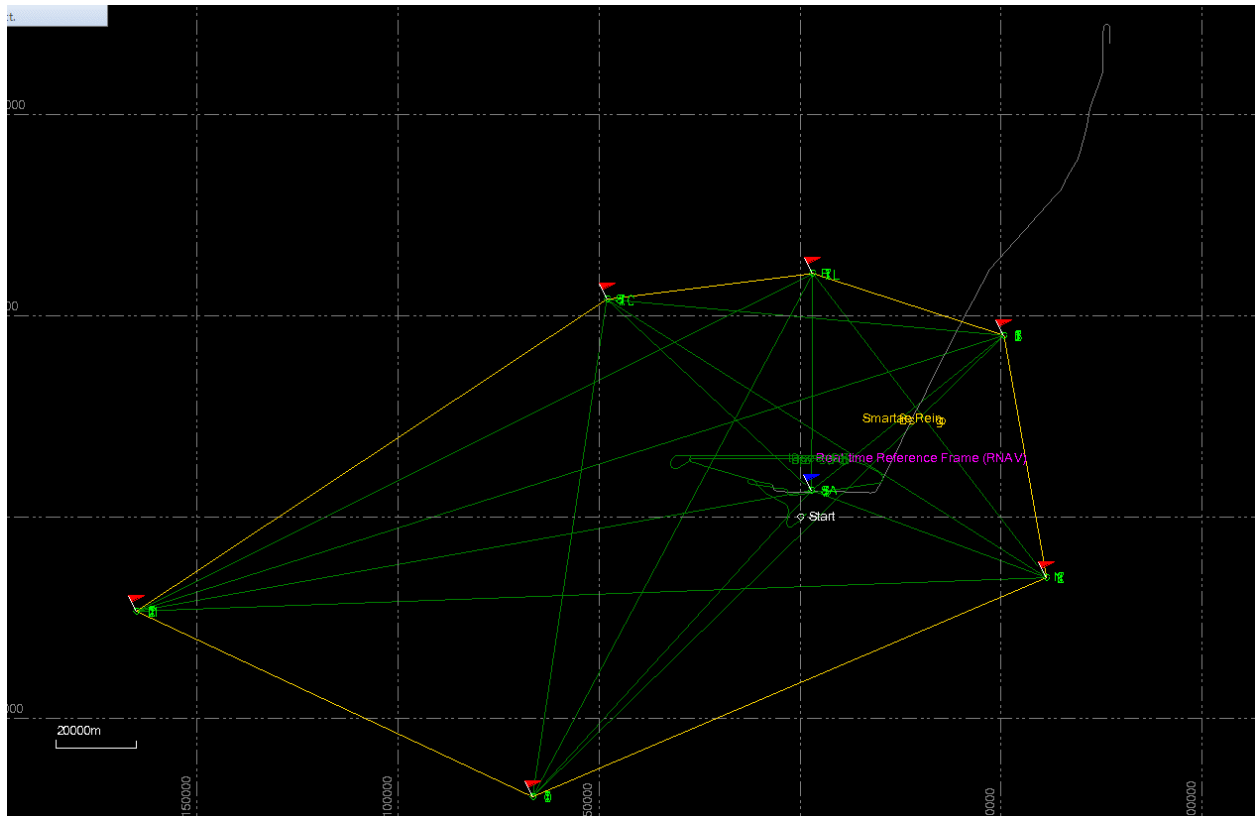
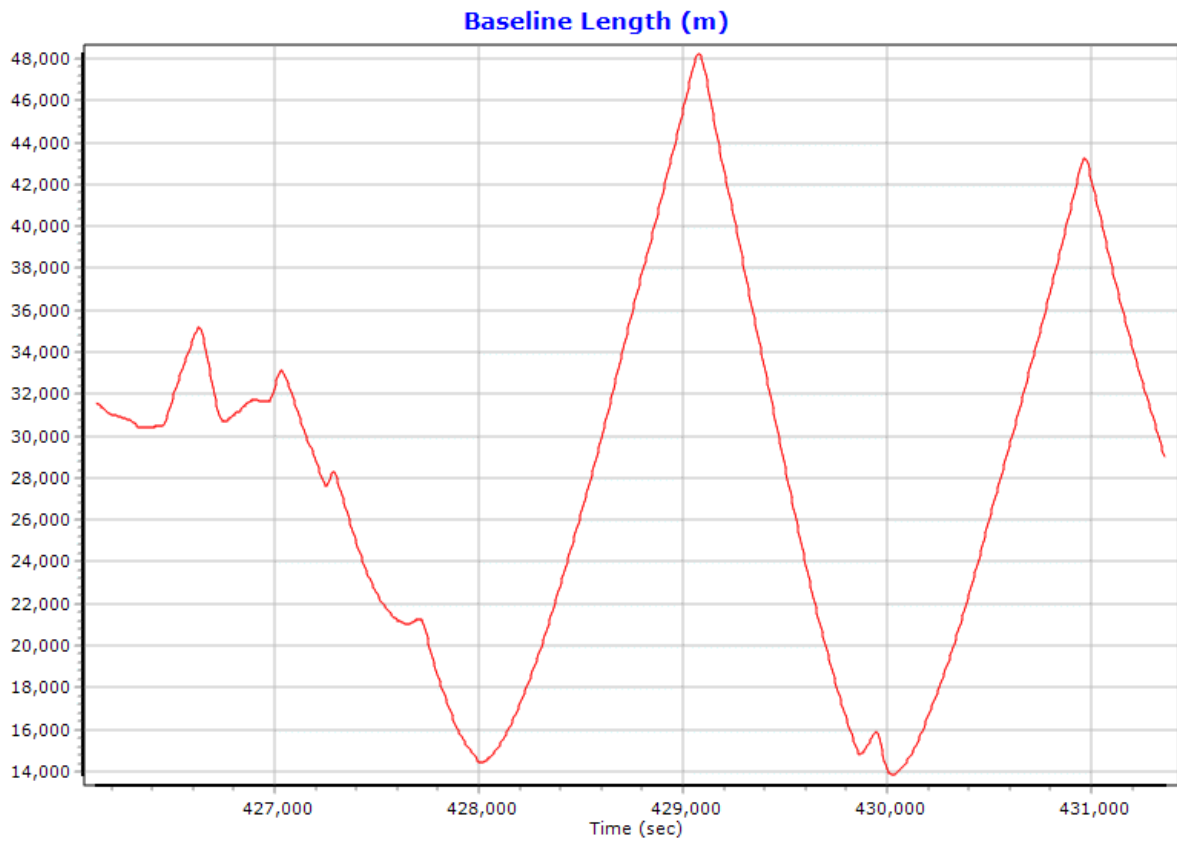
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

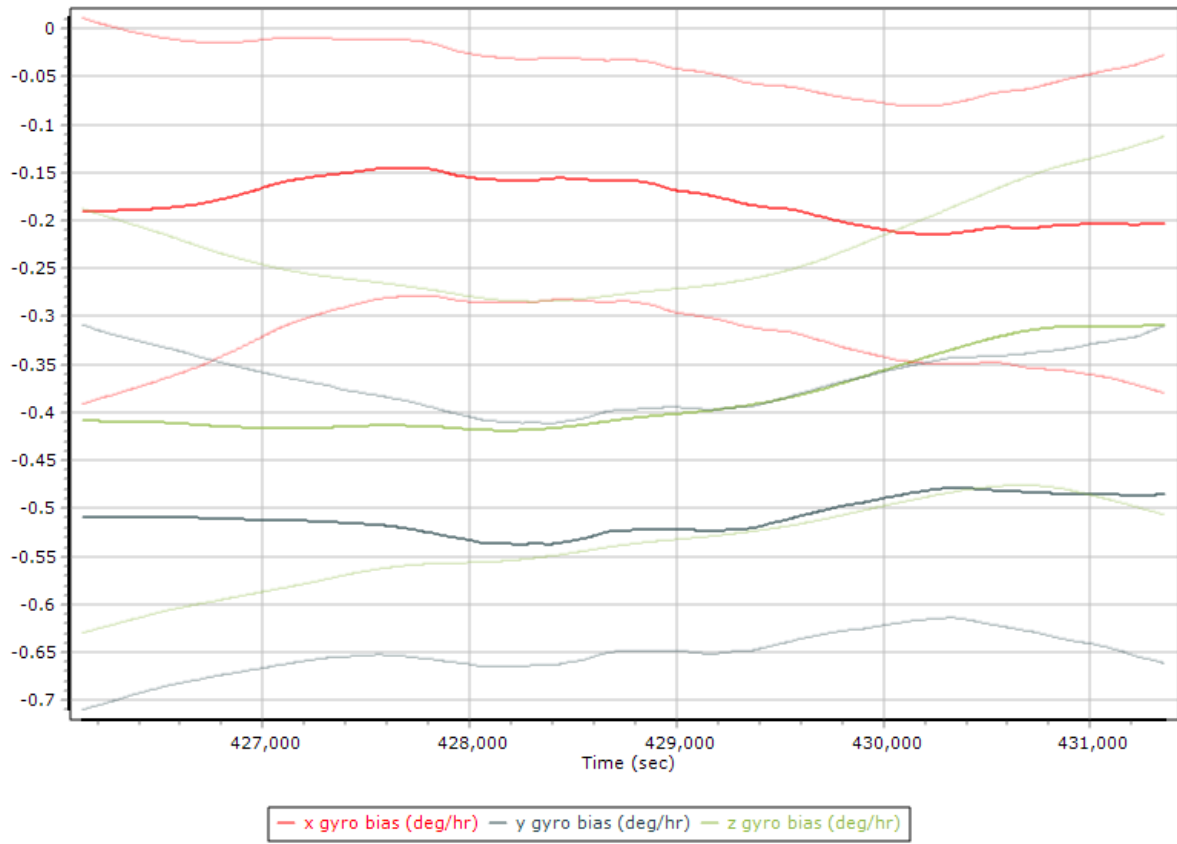
UNB18067B

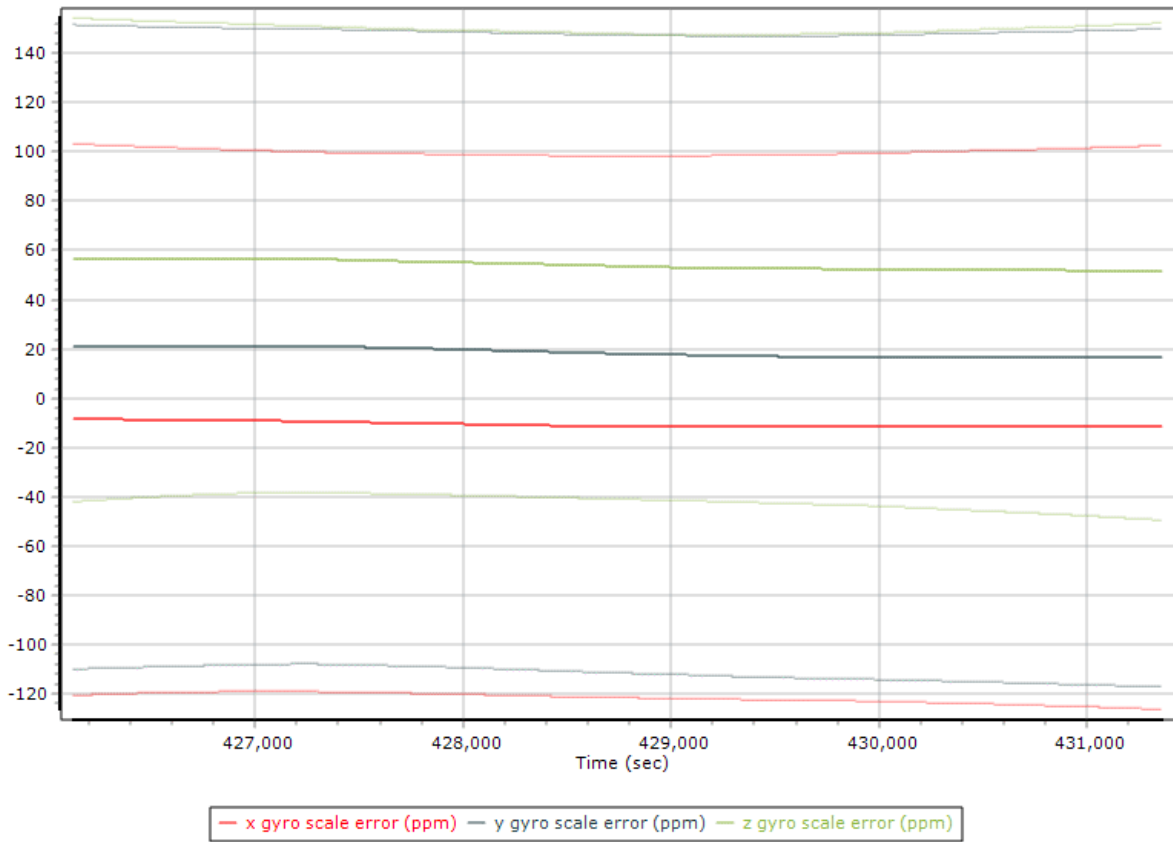












Project Settings [X]

- General Information
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- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

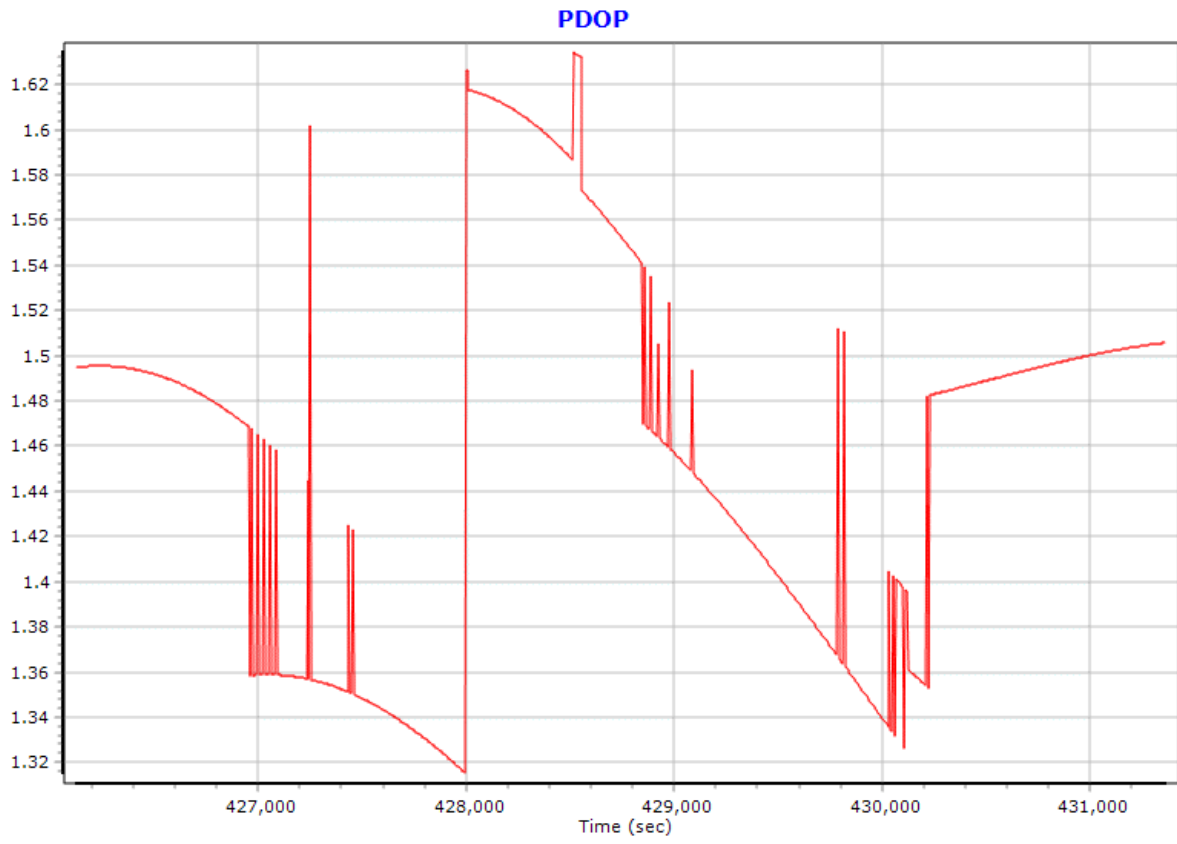
Aircraft to Reference Mounting Angles

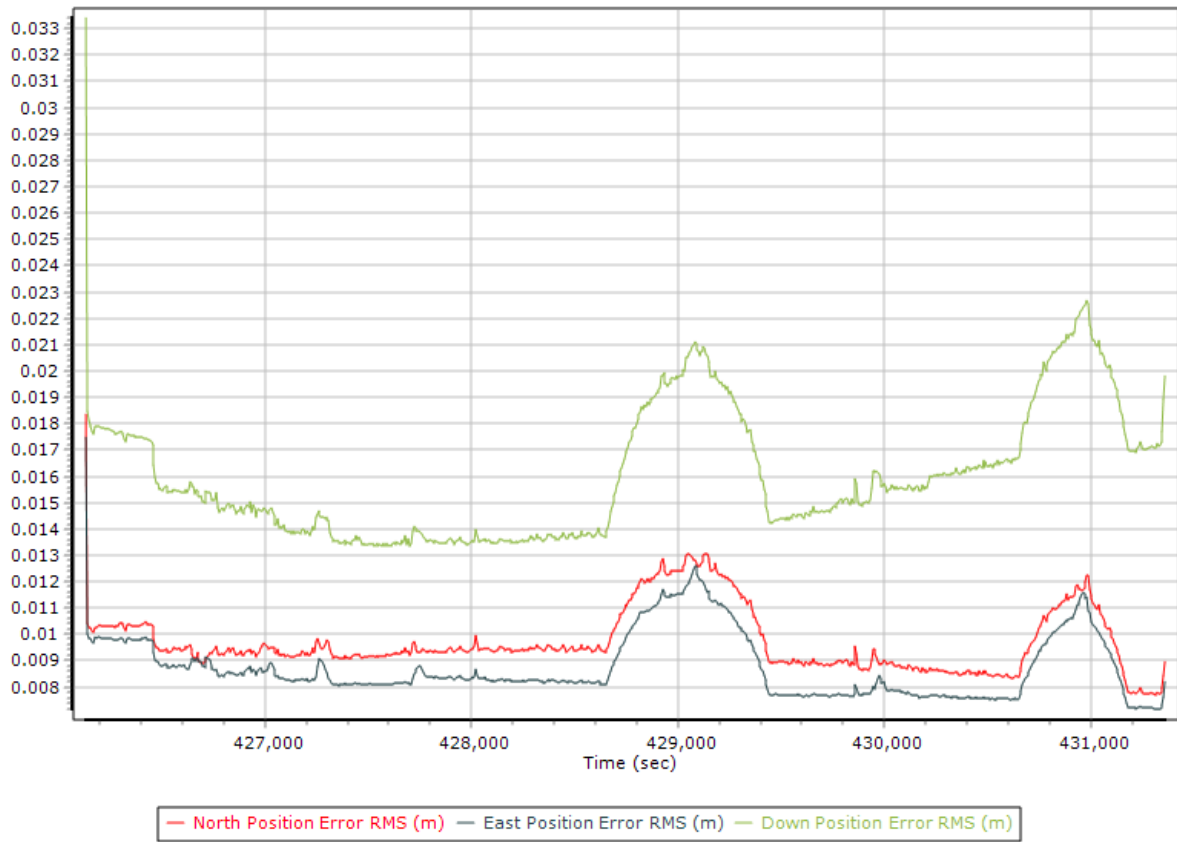
X:

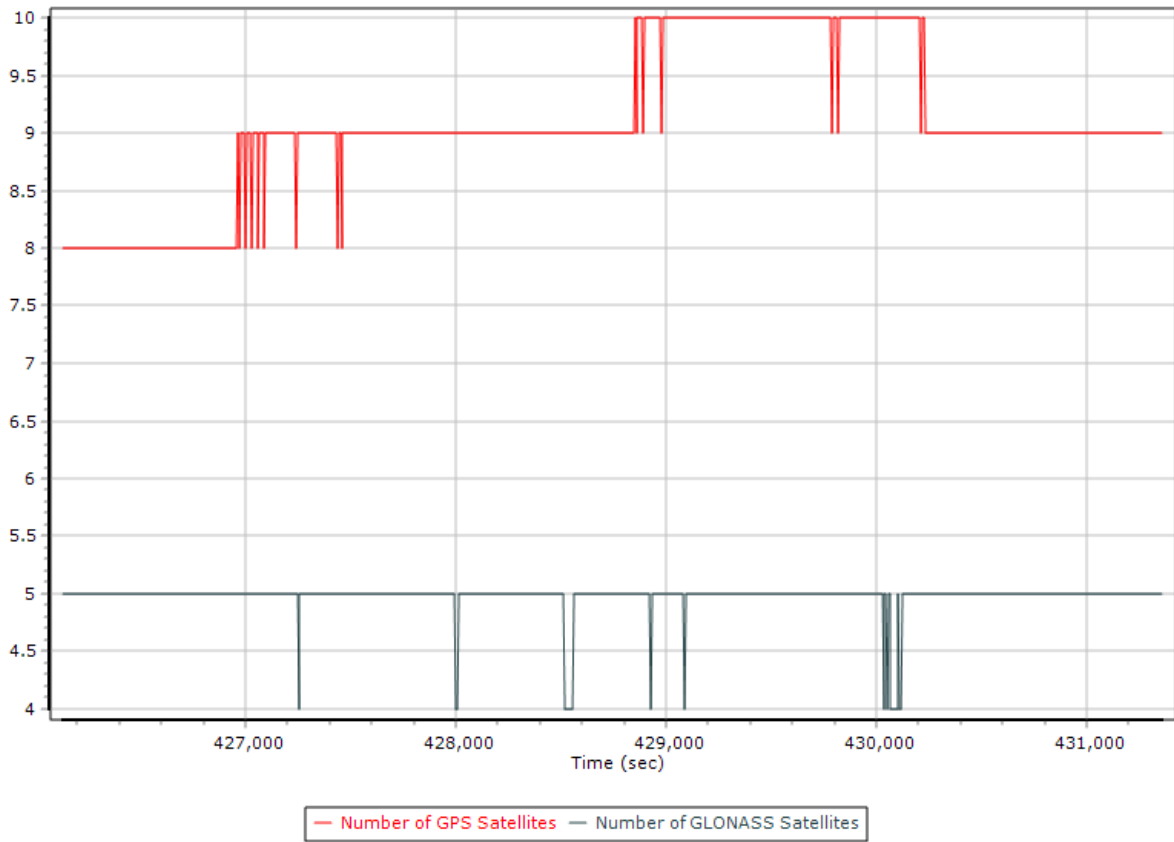
Y:

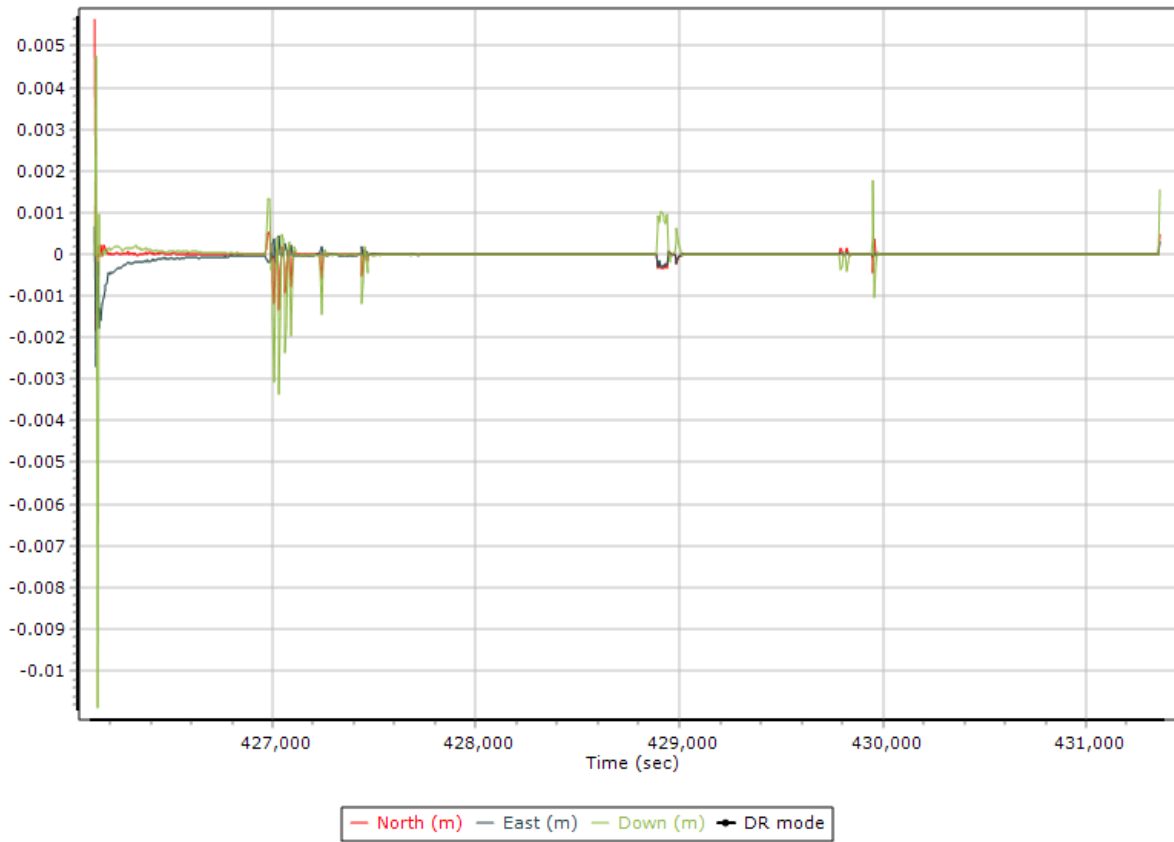
Z:

OK Cancel









Project Settings

- General Information
- Units
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- Satellite Selection
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 - Timing
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 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

Timing

Start: 425875.000
End: 431367.533

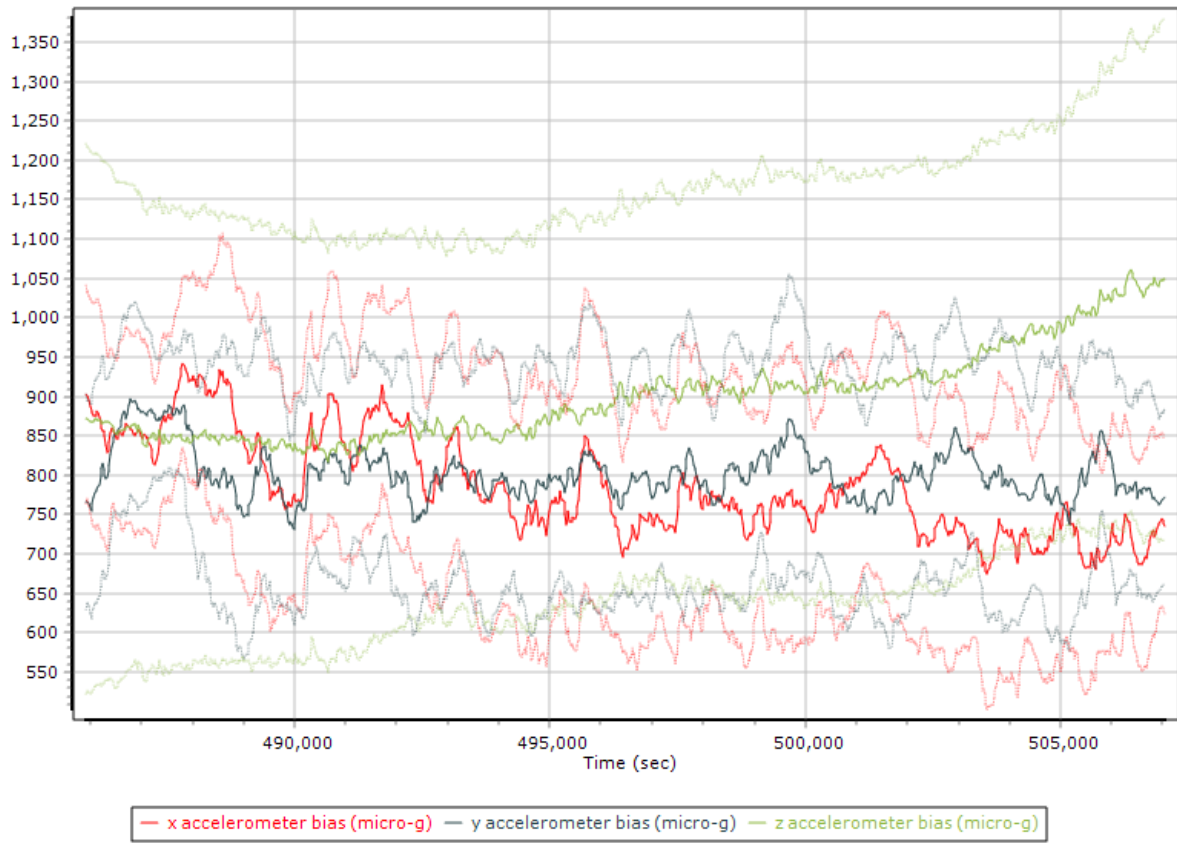
Entire time interval
 Seconds of start week

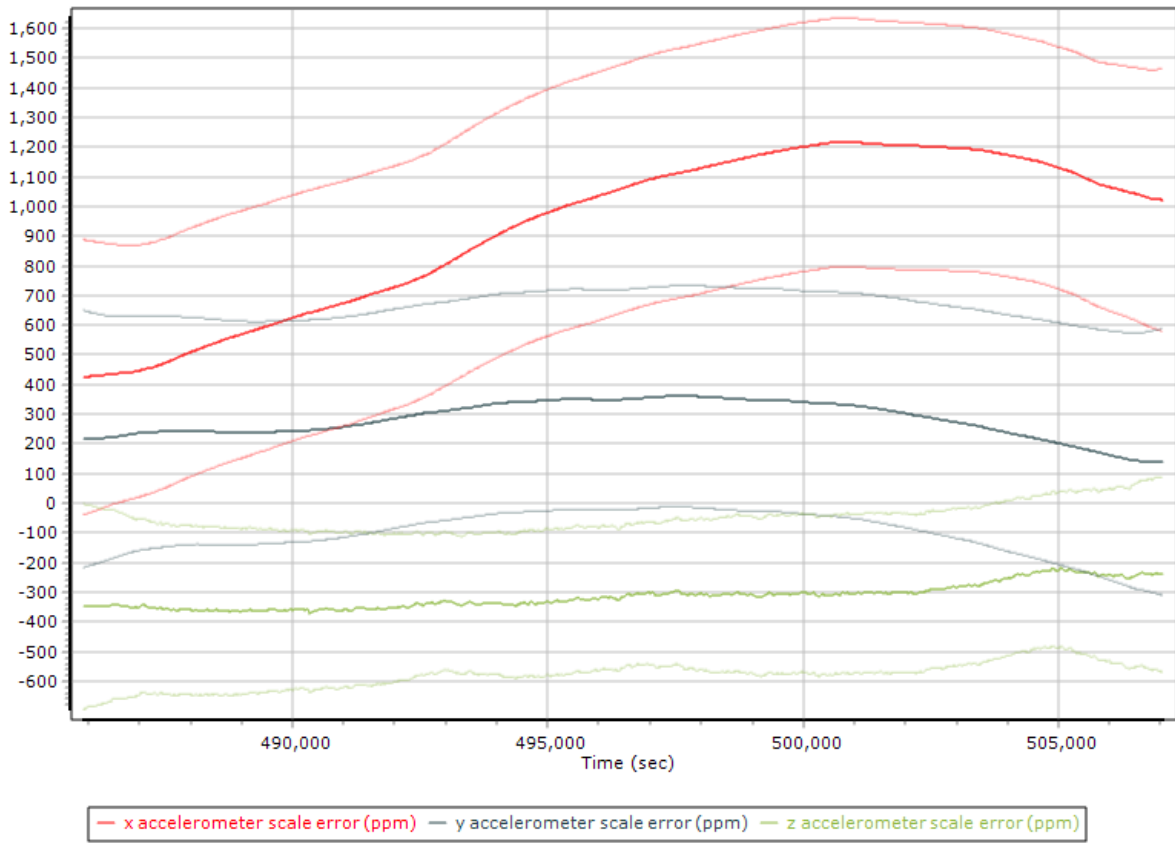
UTC Offset: 18.000

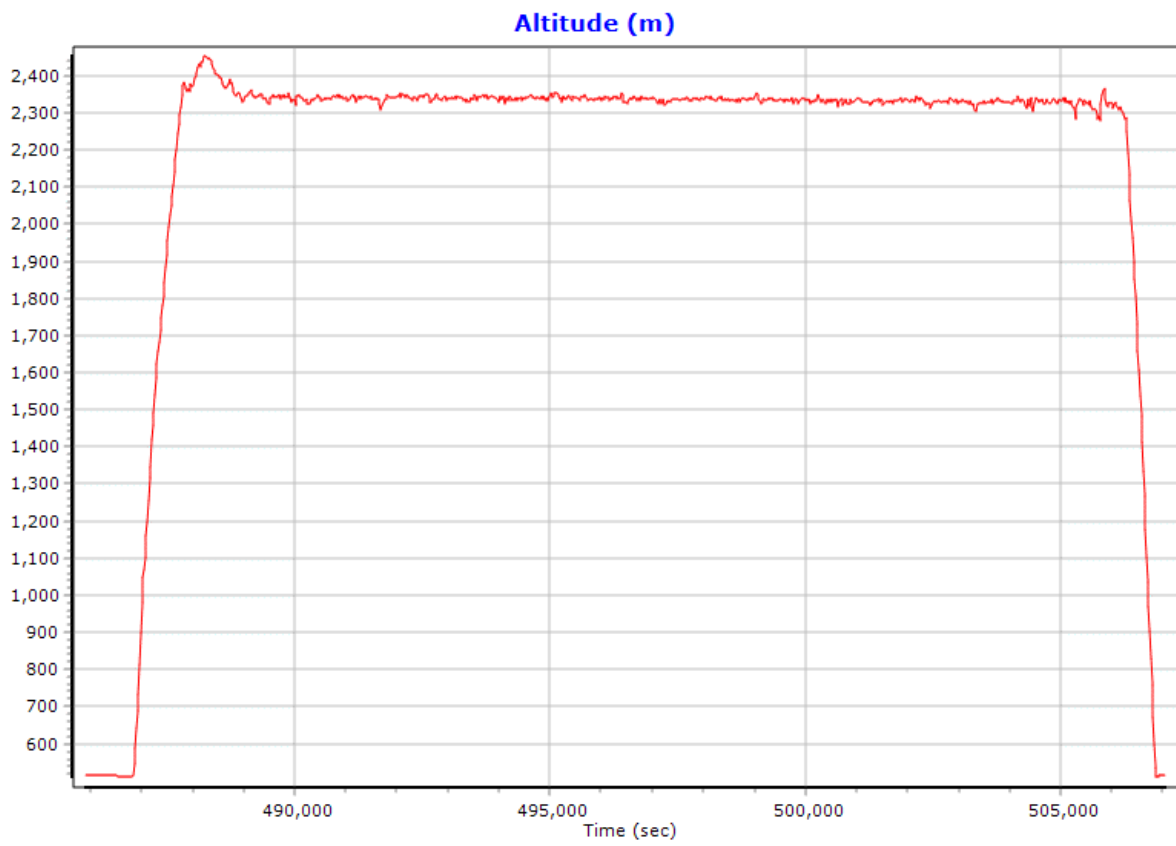
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel

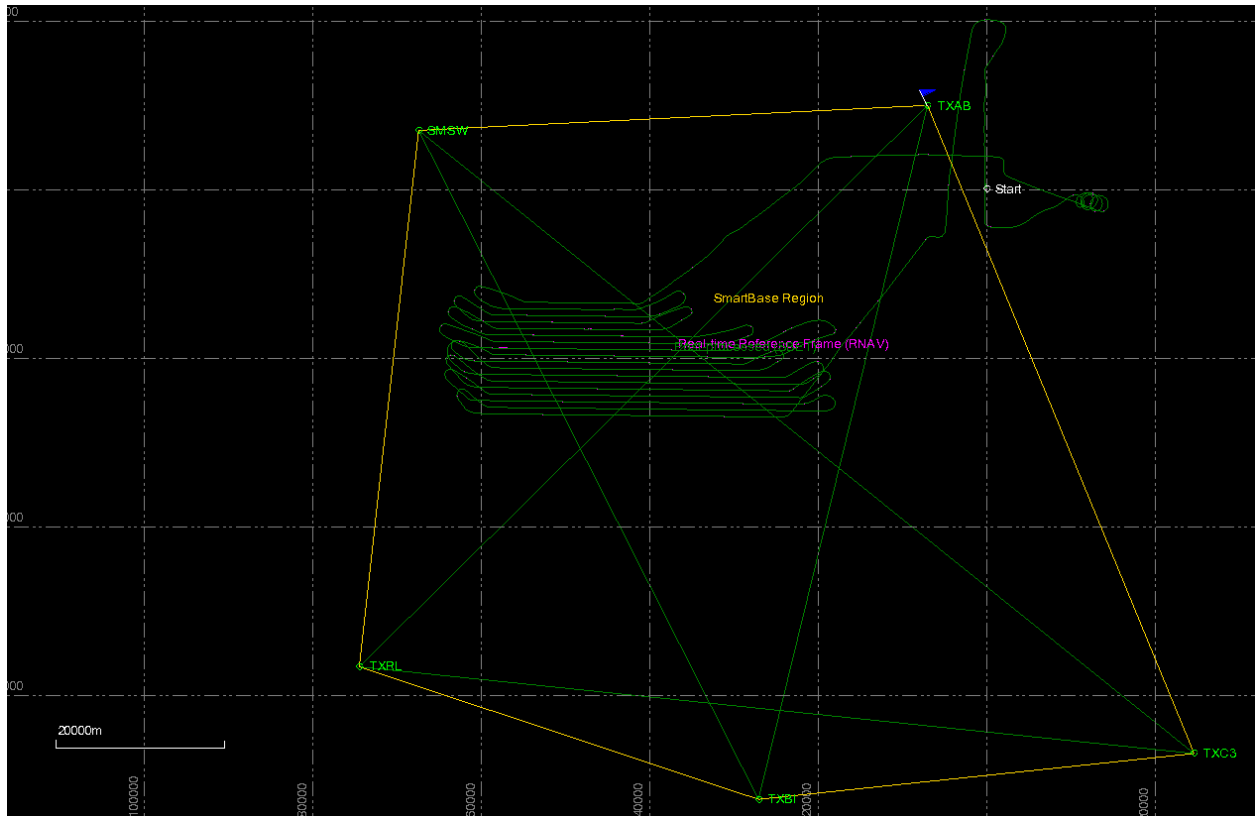
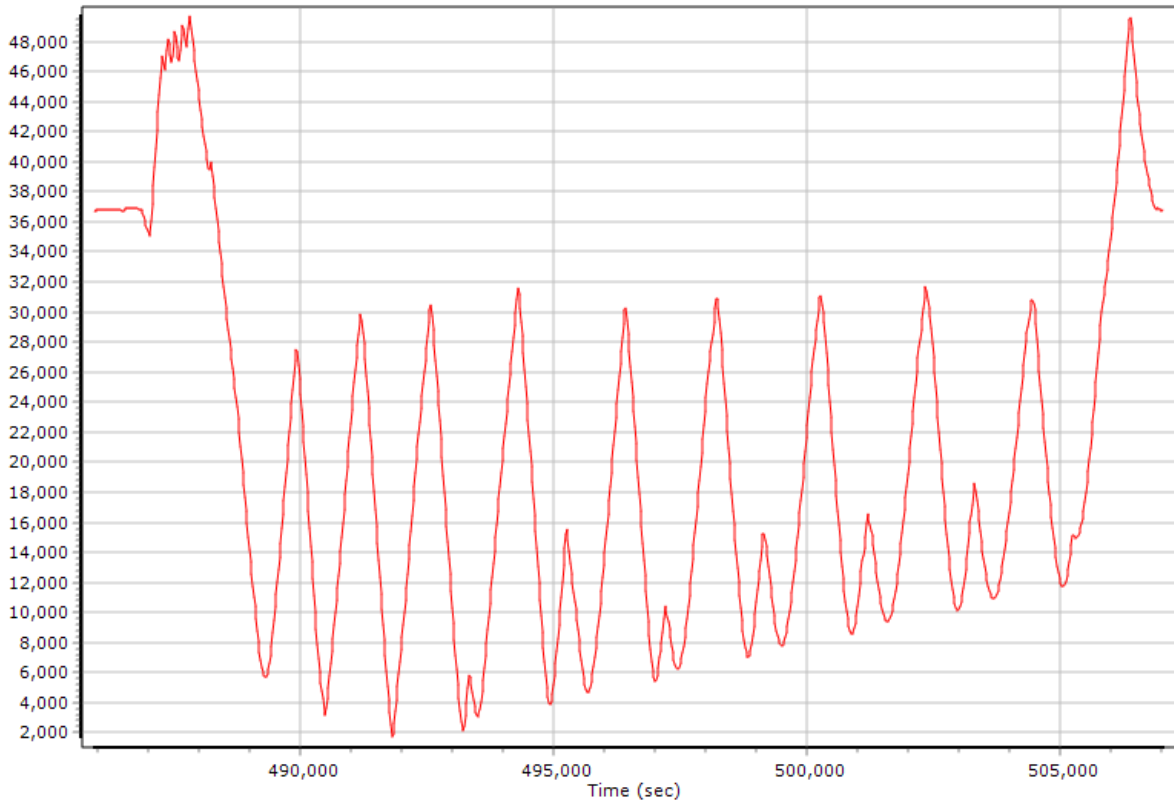
UNB18o68A

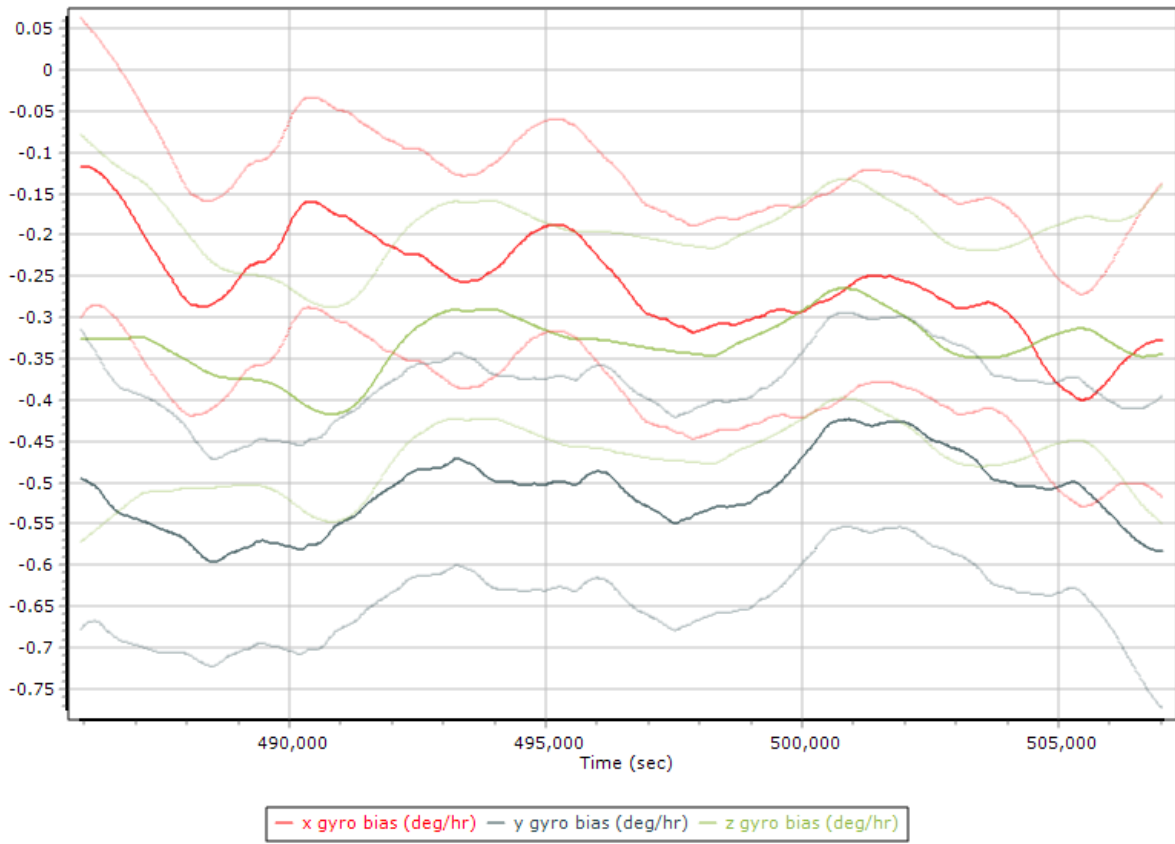


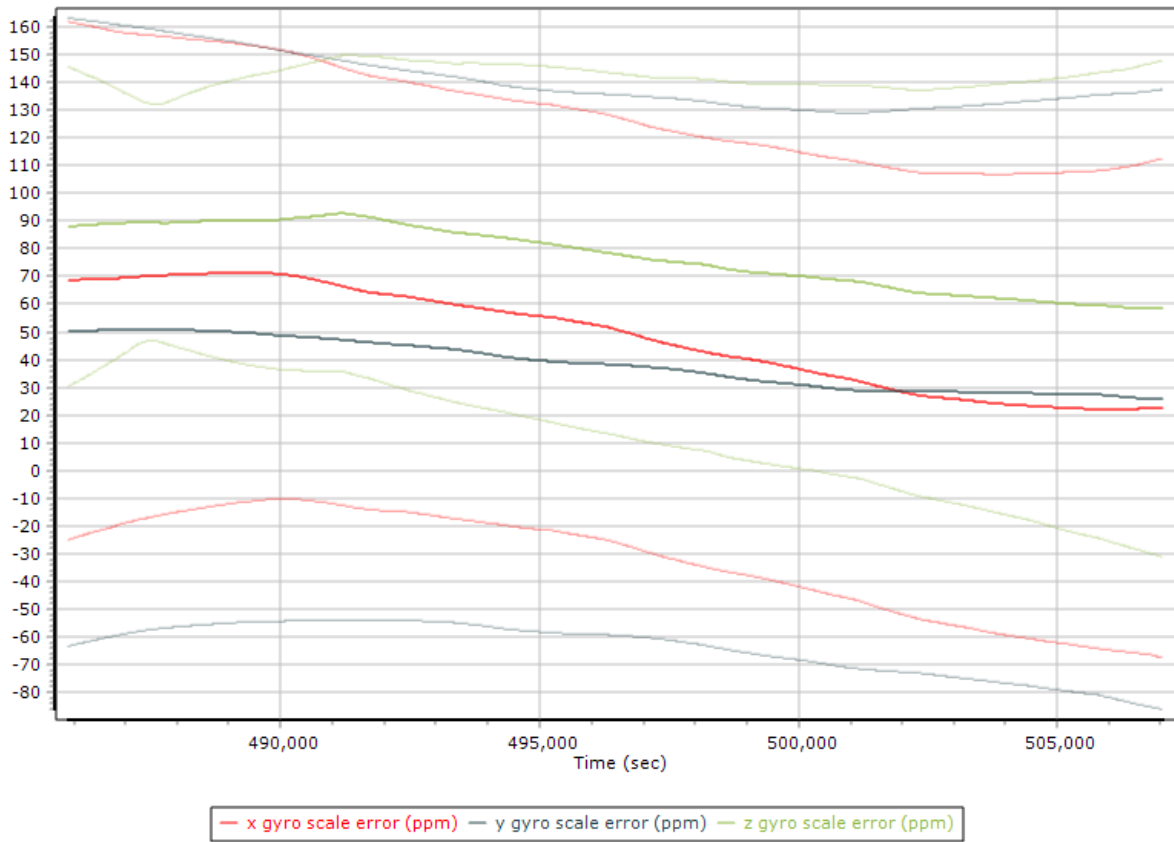




Baseline Length (m)







Project Settings ✕

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- Export
- Camera
- LIDAR
- SAR

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

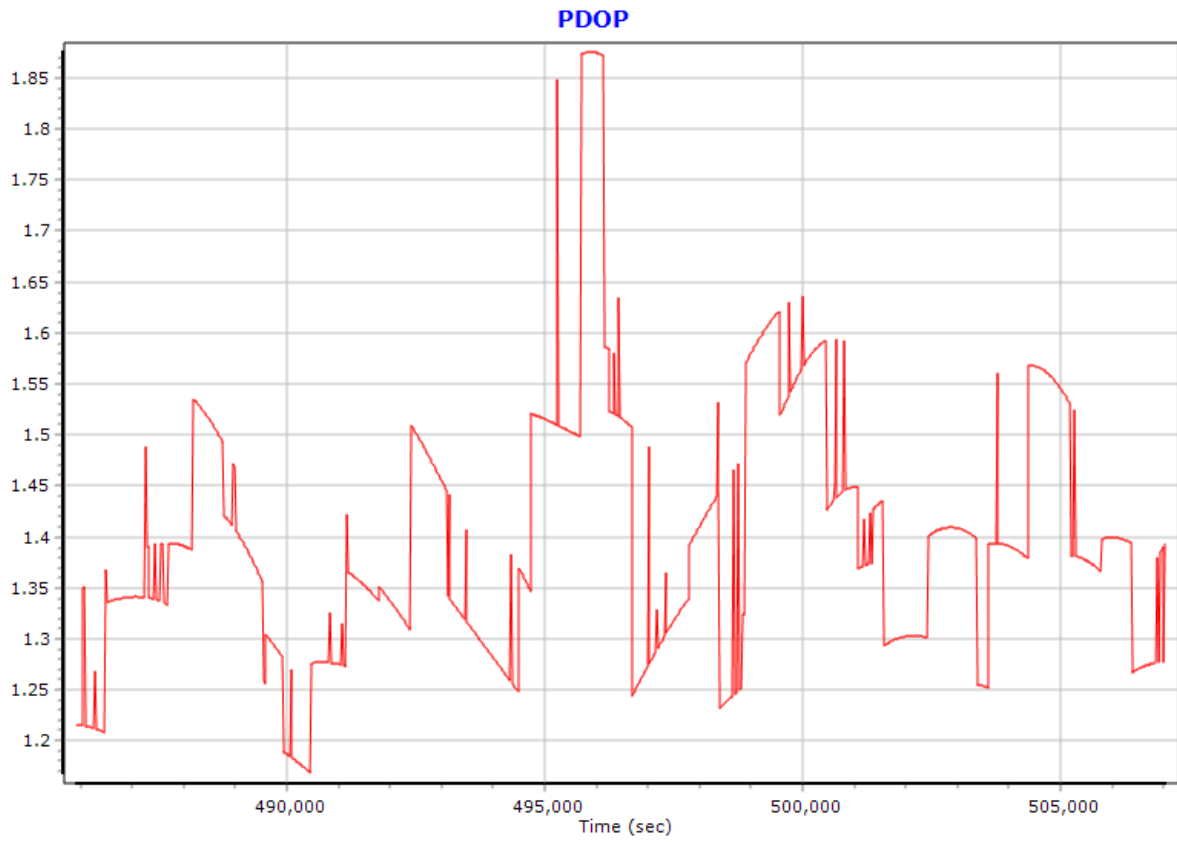
<3cm 10cm 50cm 1m 10m

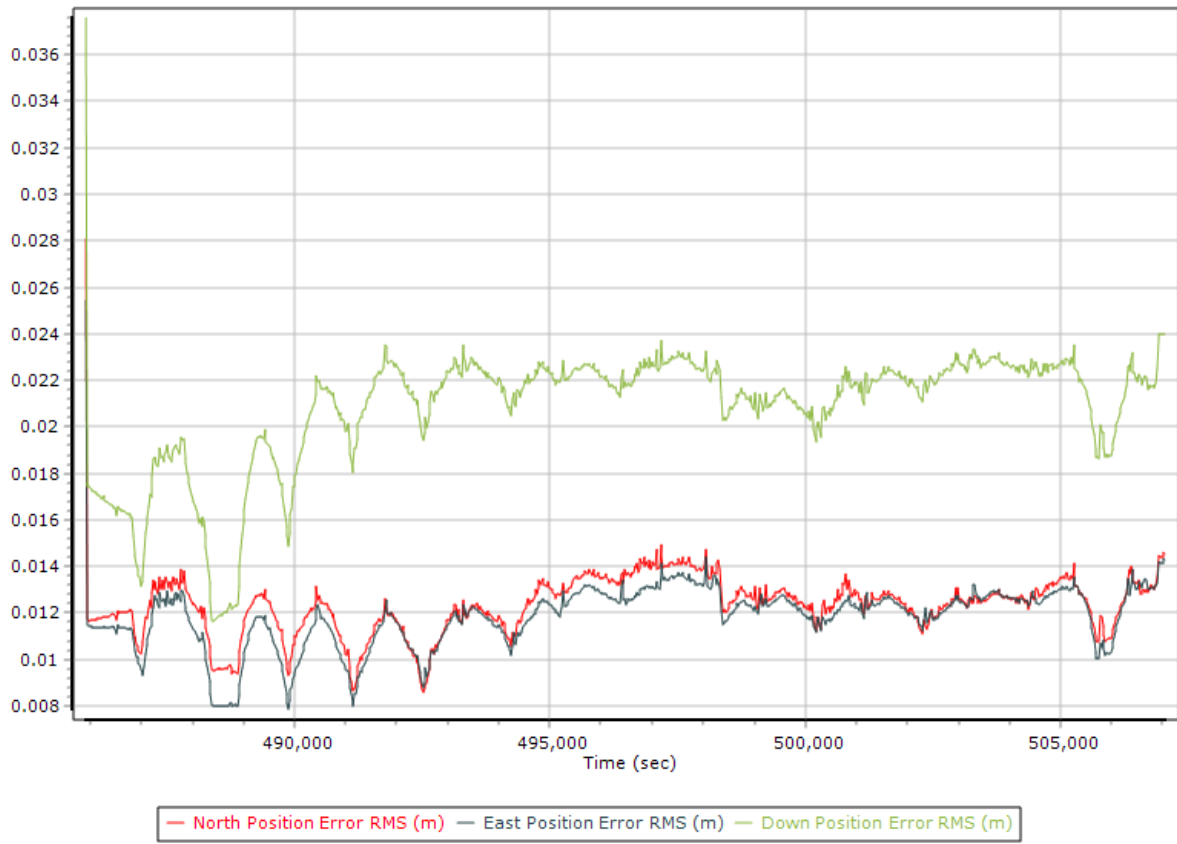
Aircraft to Reference Mounting Angles

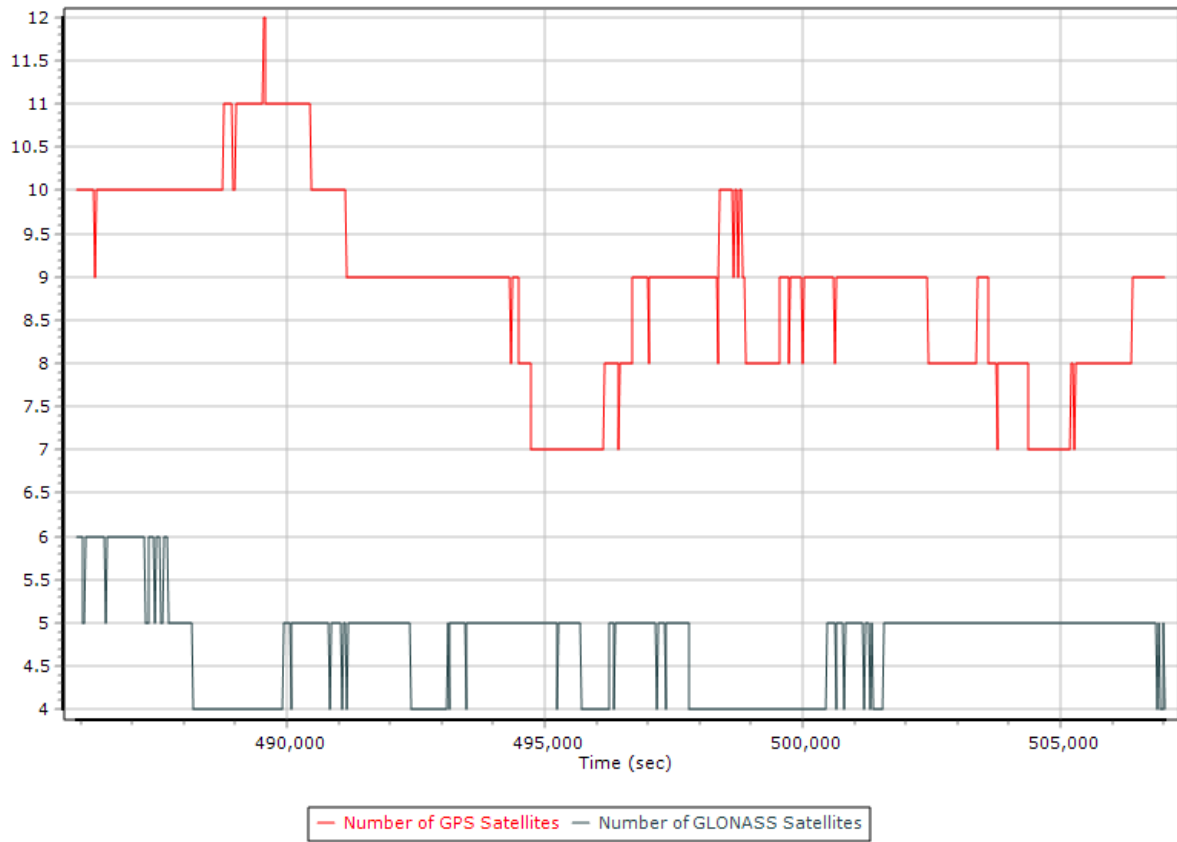
X:

Y:

Z:









Project Settings

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

Timing

Start: 485599.000
End: 507069.000

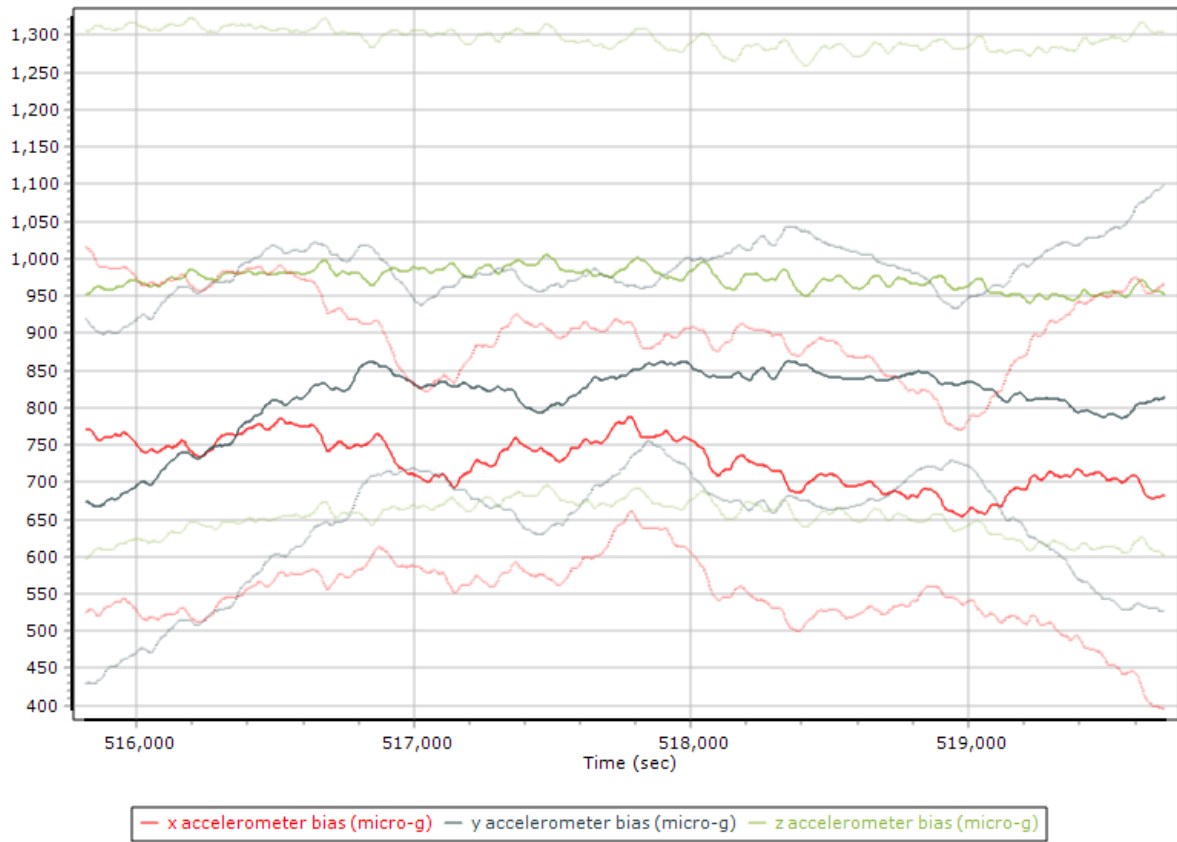
Entire time interval
 Seconds of start week

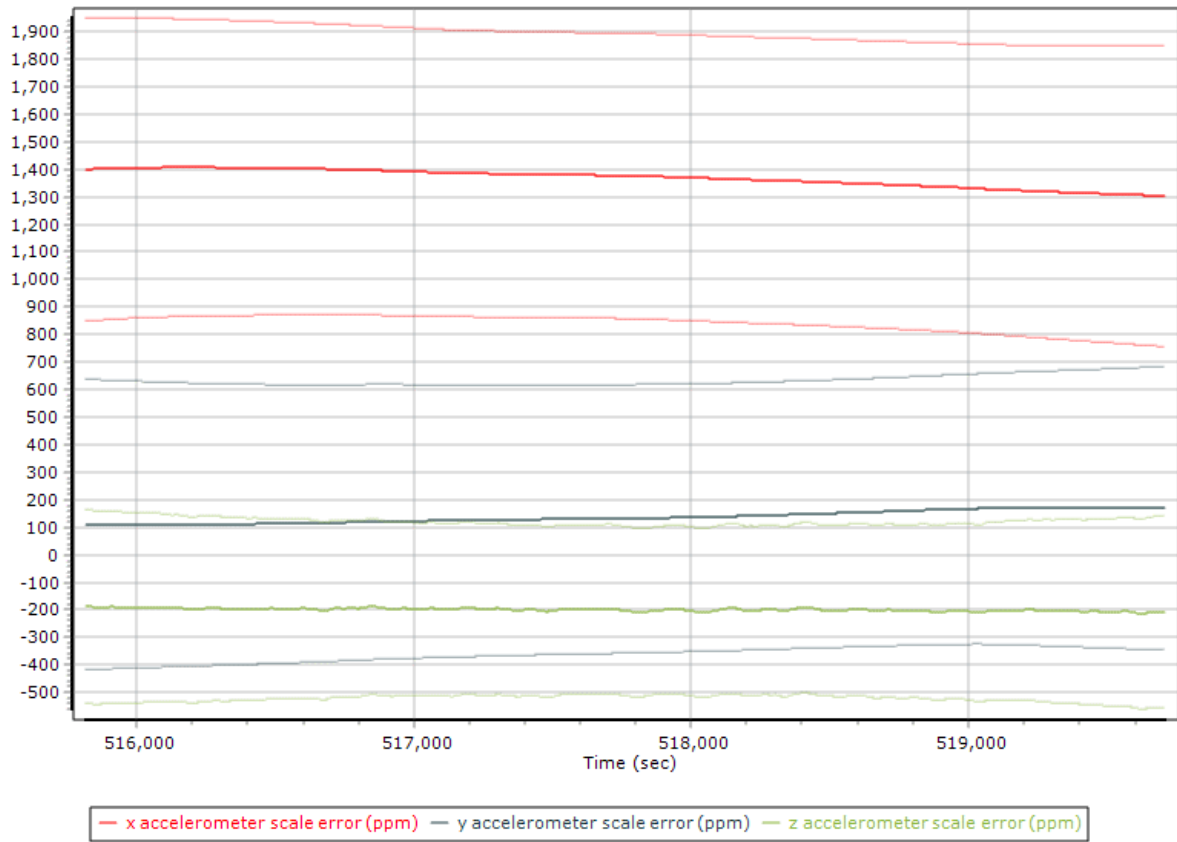
UTC Offset: 18.000

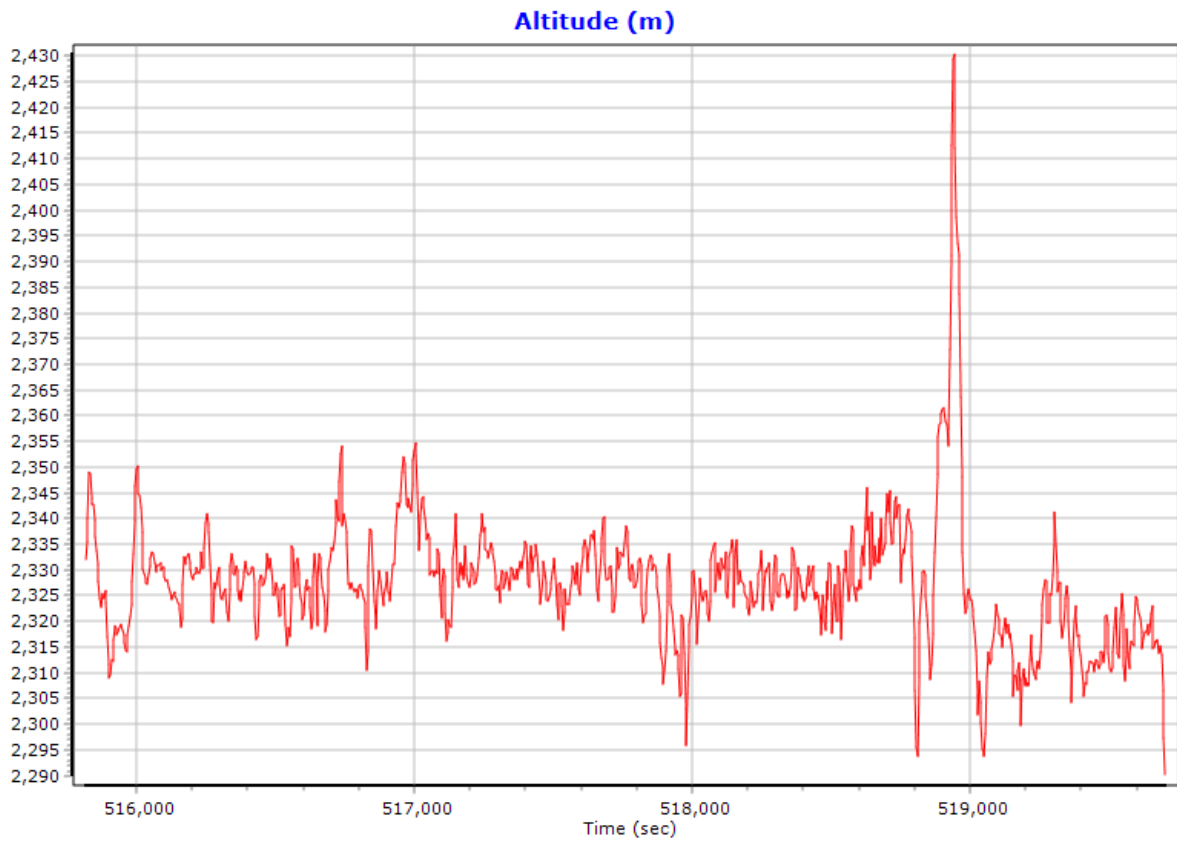
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

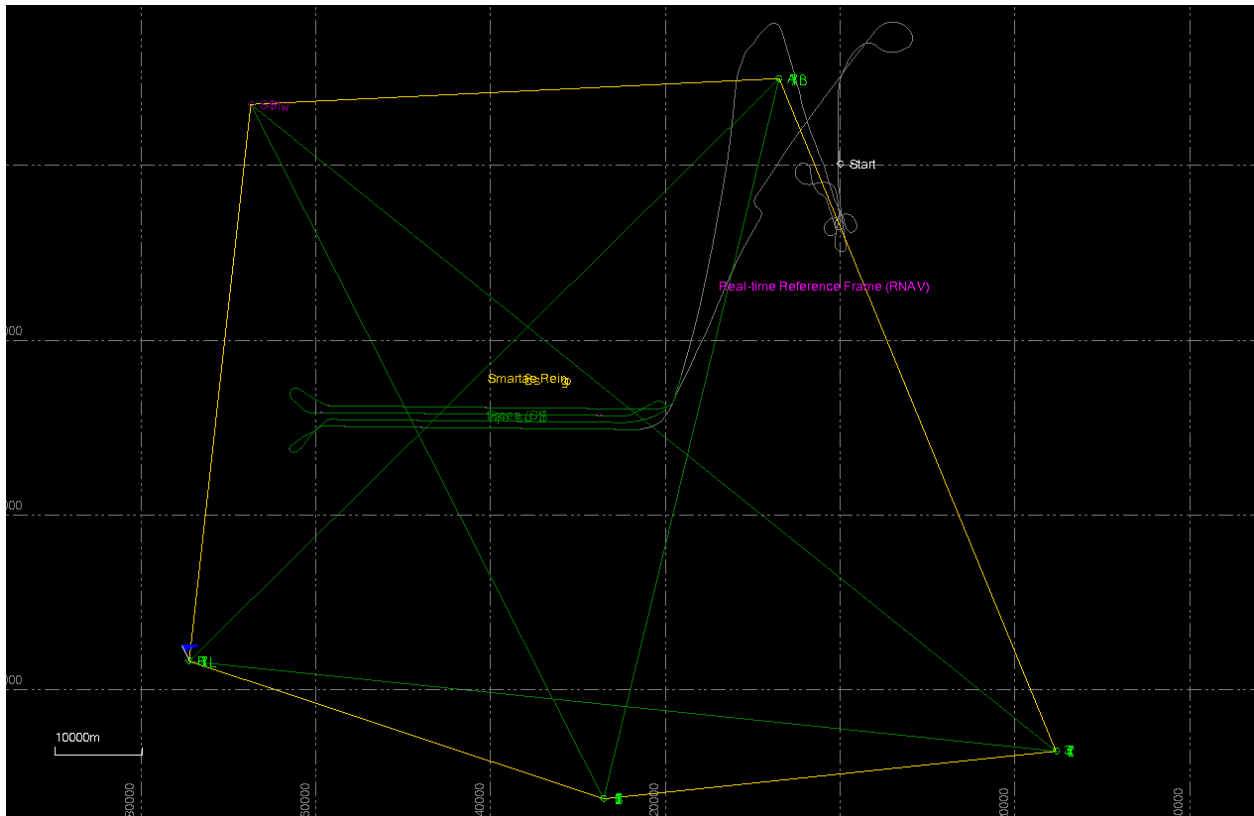
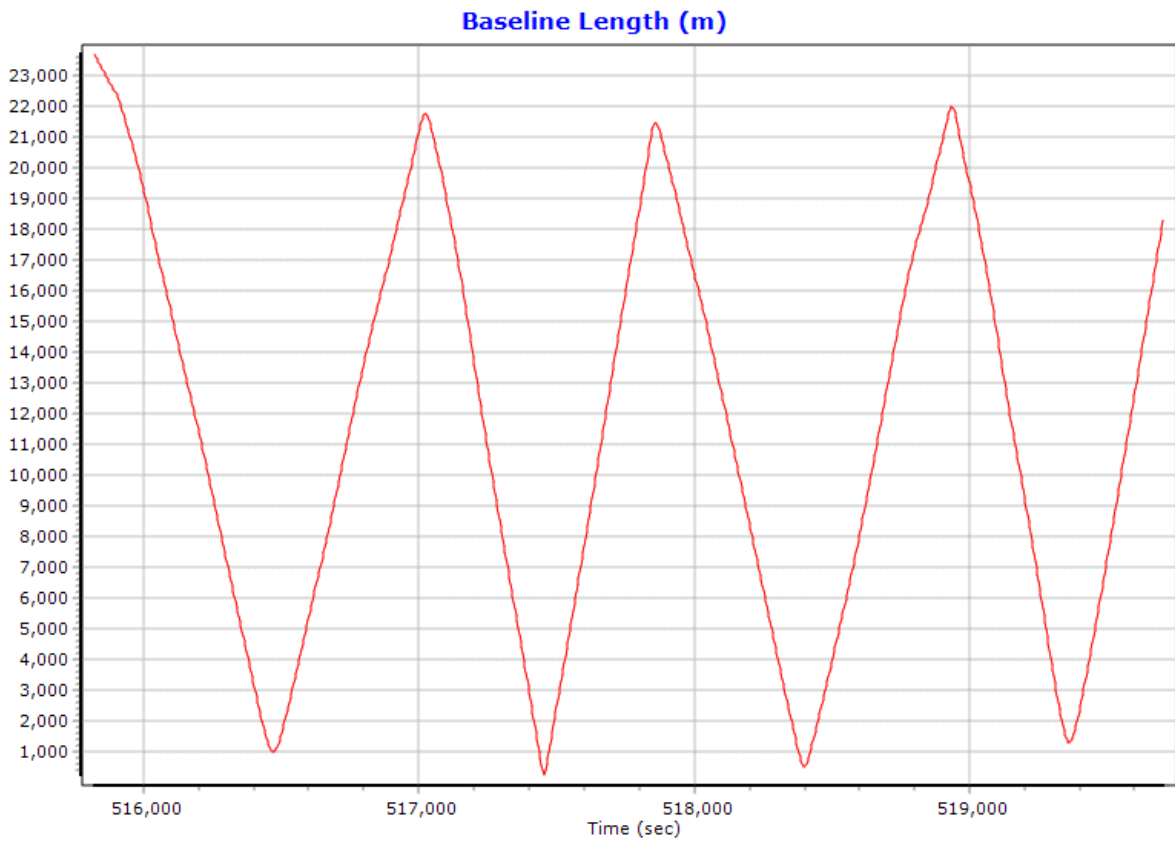
OK Cancel

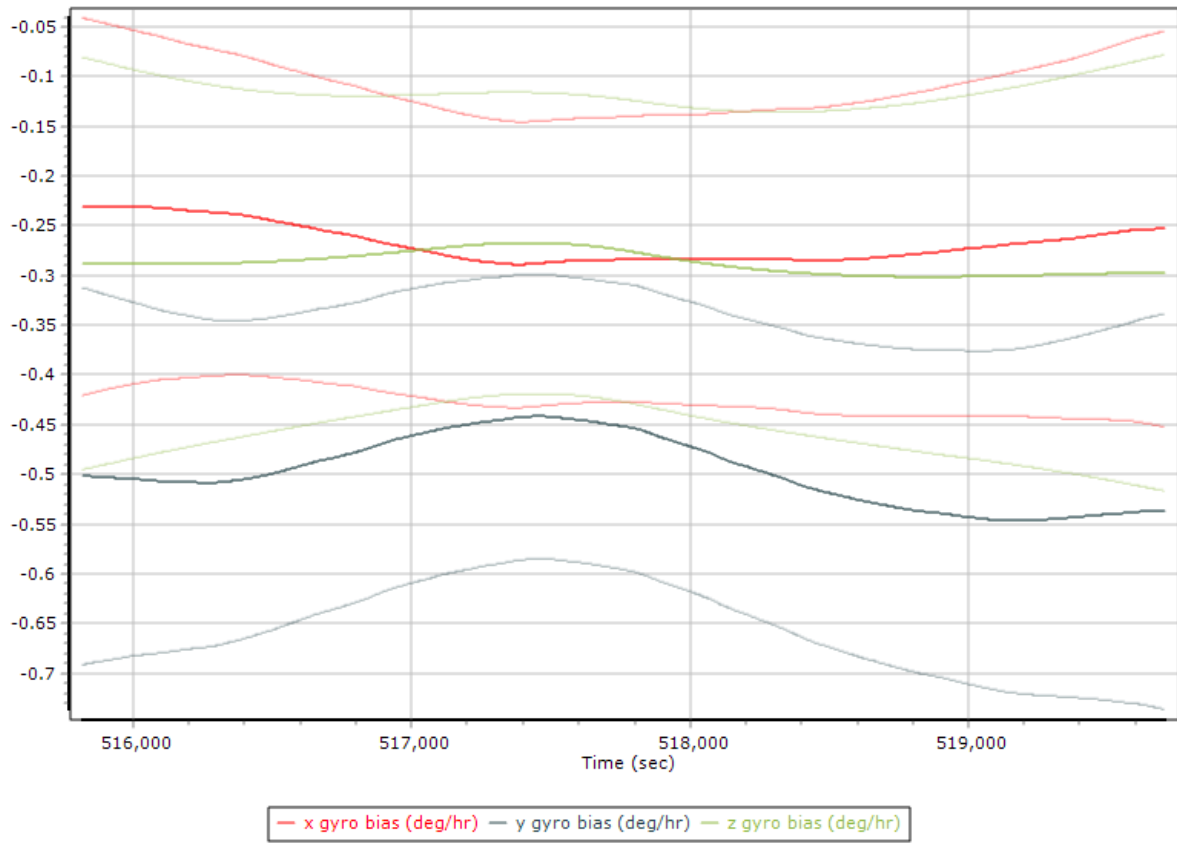
UNB18068B

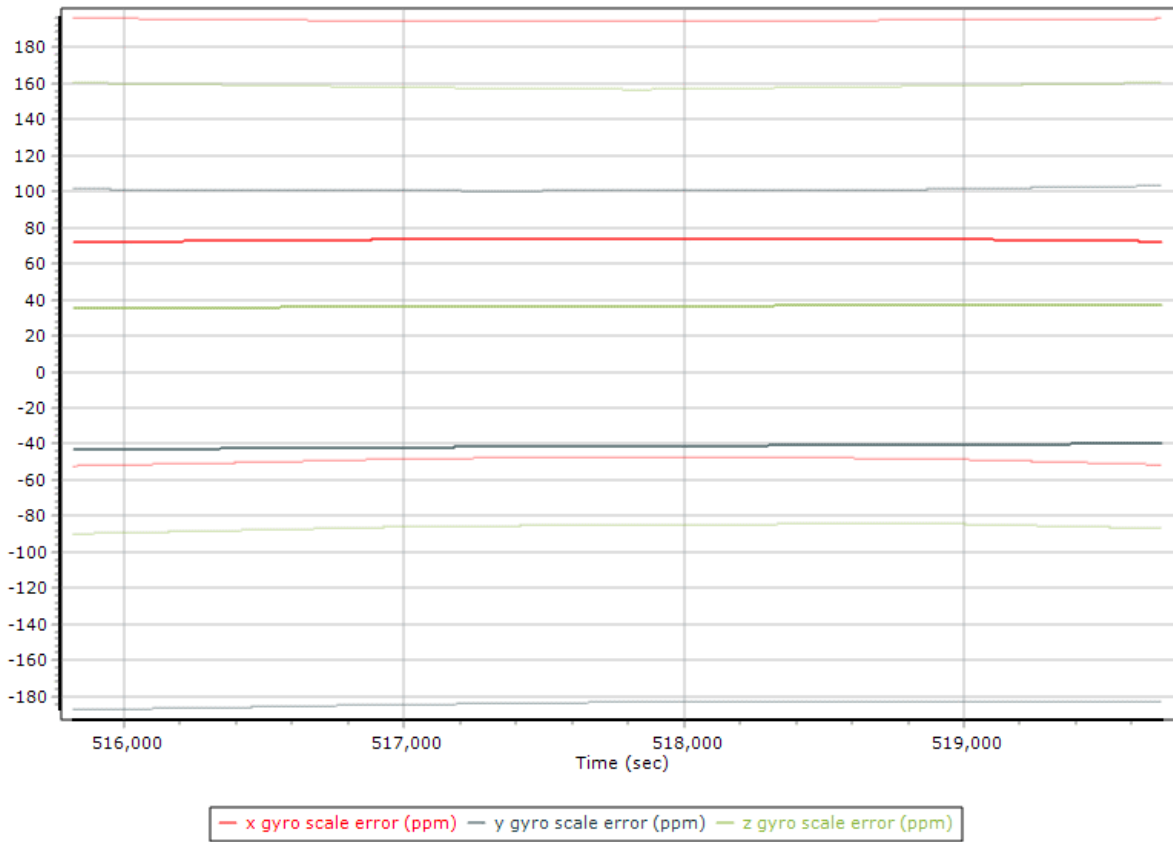












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

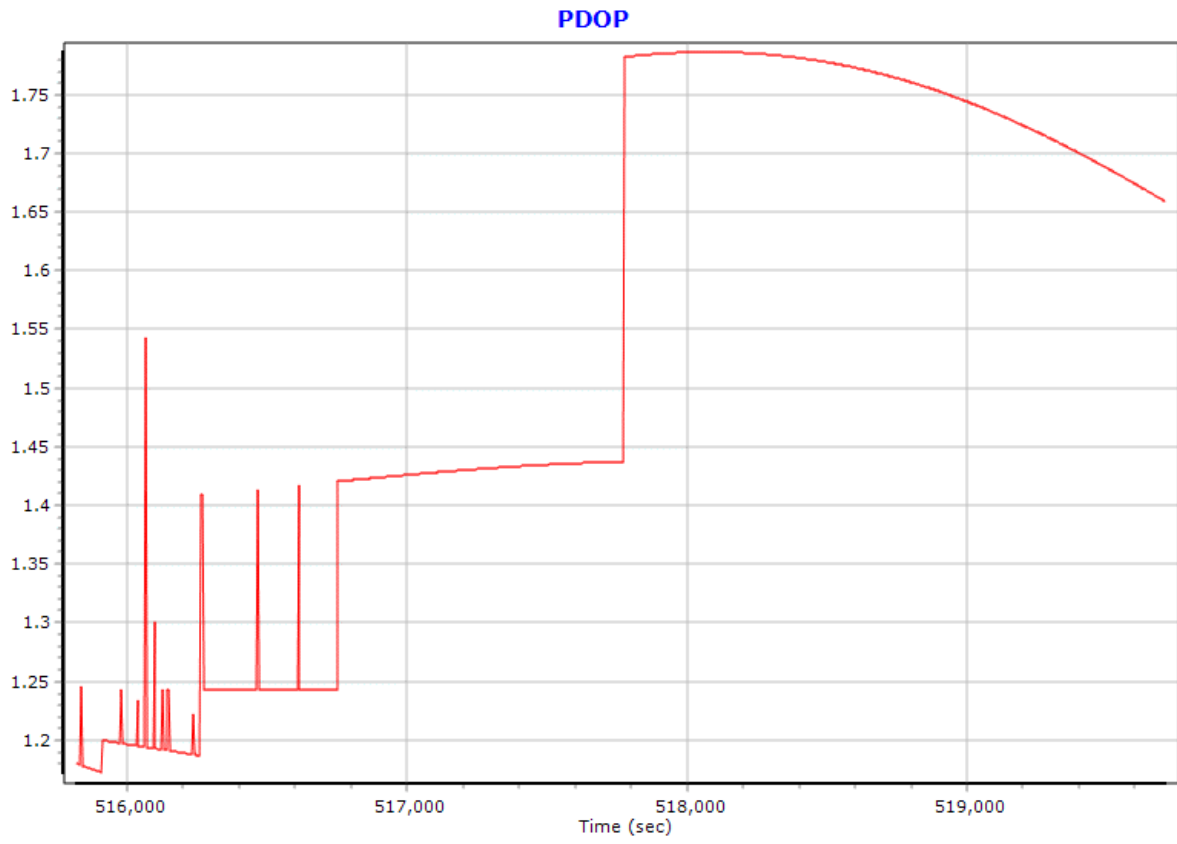
<3cm 10cm 50cm 1m 10m

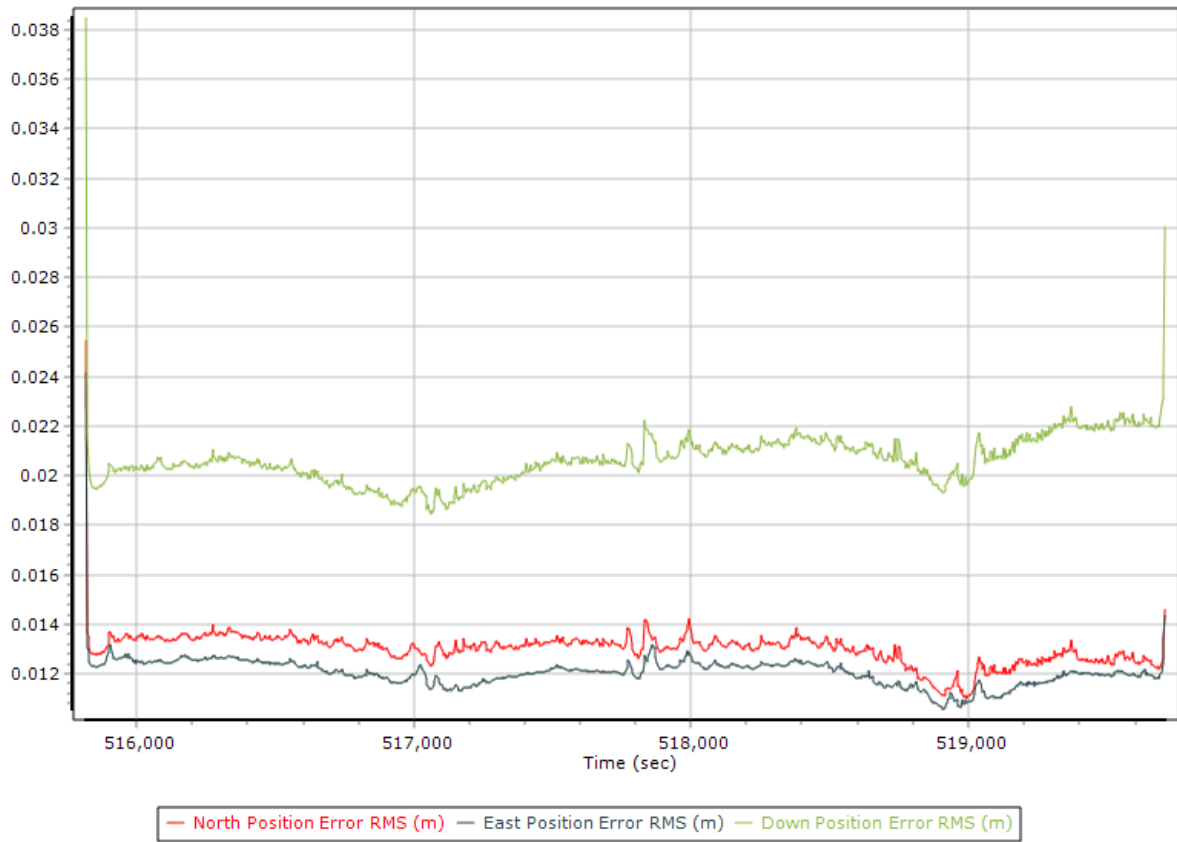
Aircraft to Reference Mounting Angles

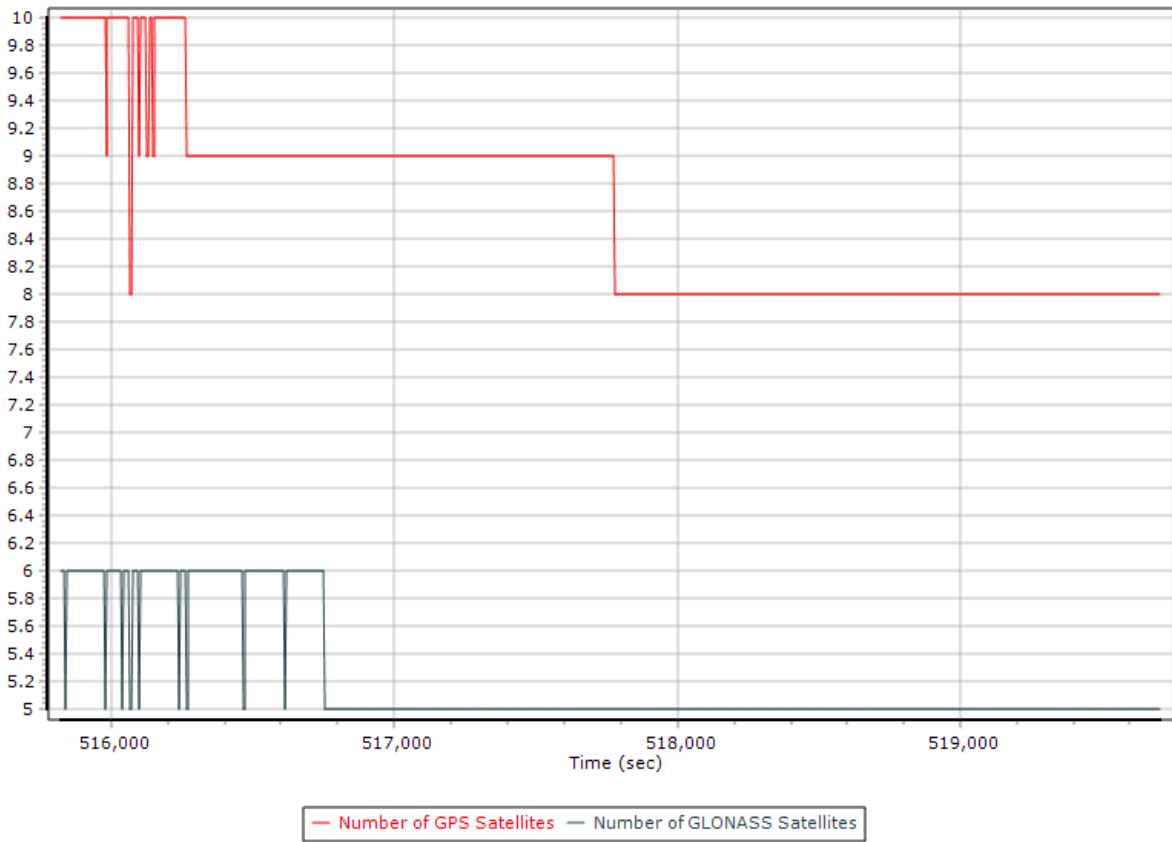
X:

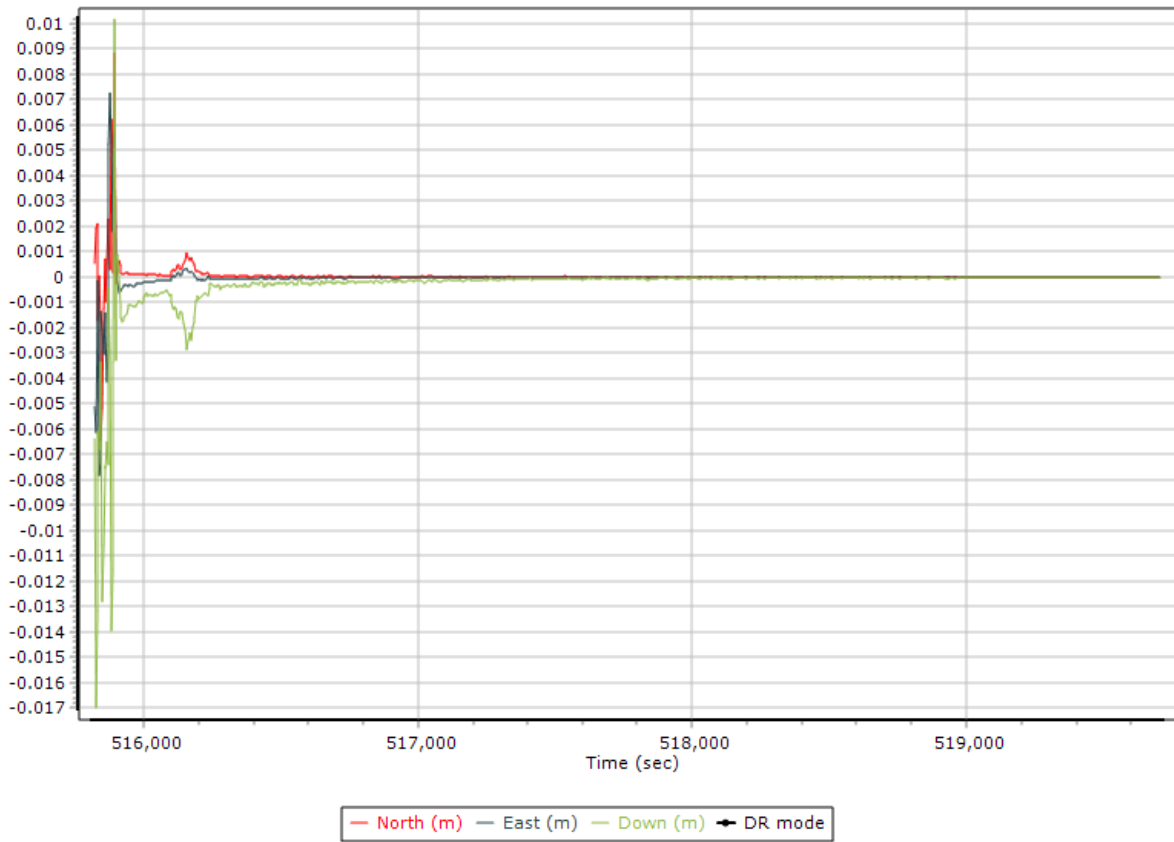
Y:

Z:









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

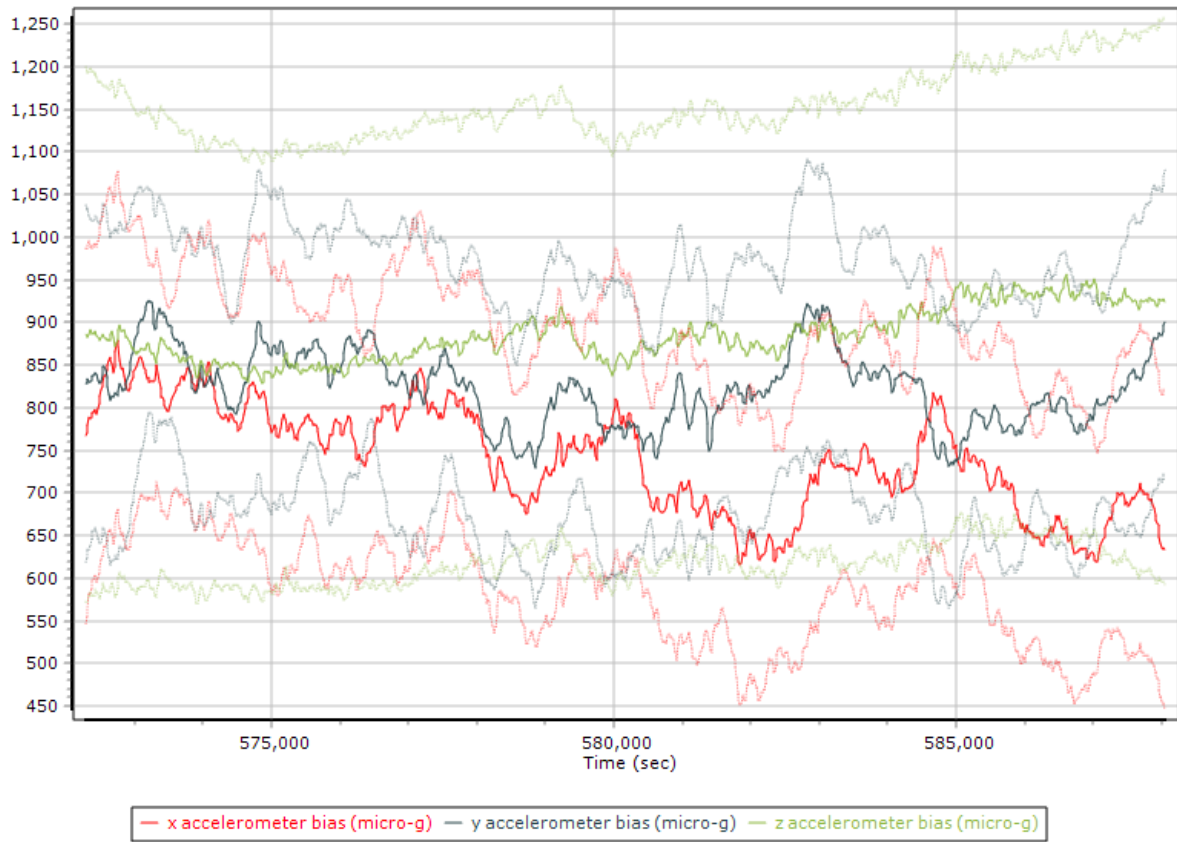
Timing

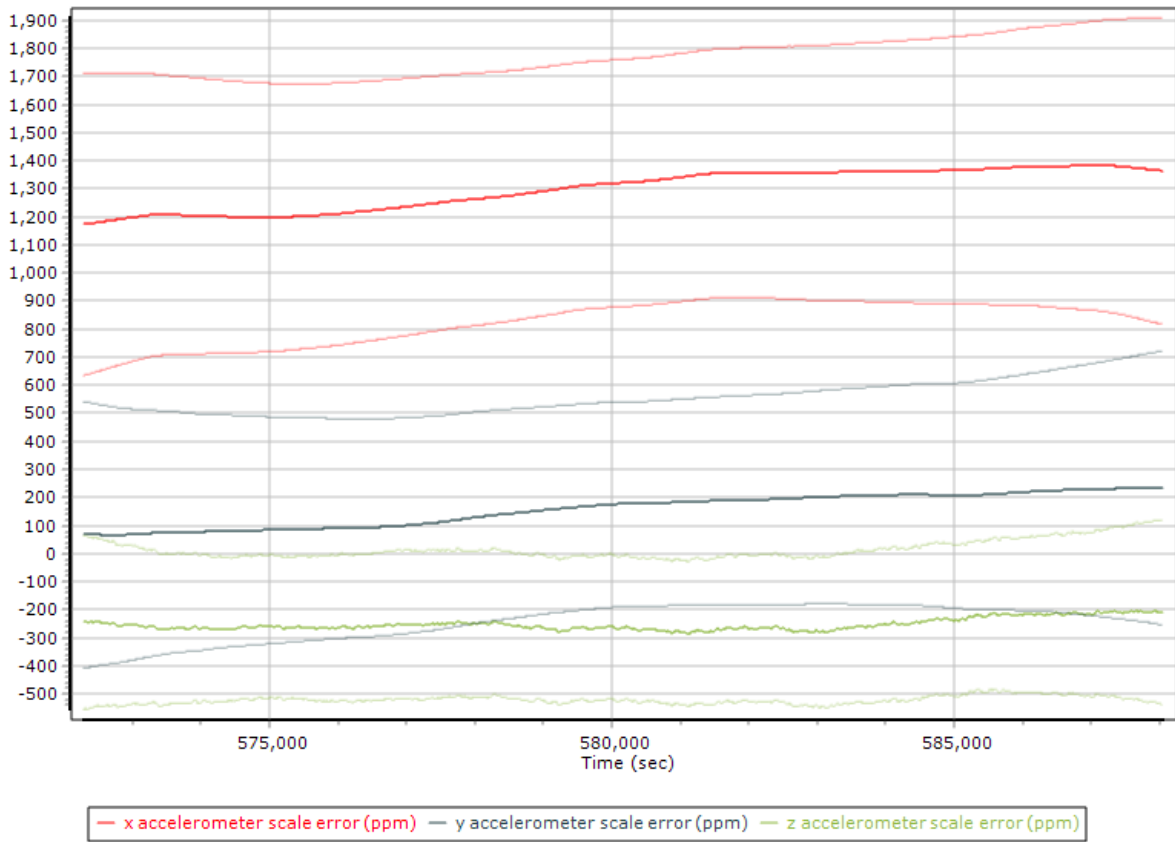
Start: 515818.398
 End: 519708.546
 Entire time interval
 Seconds of start week
 UTC Offset: 18.000

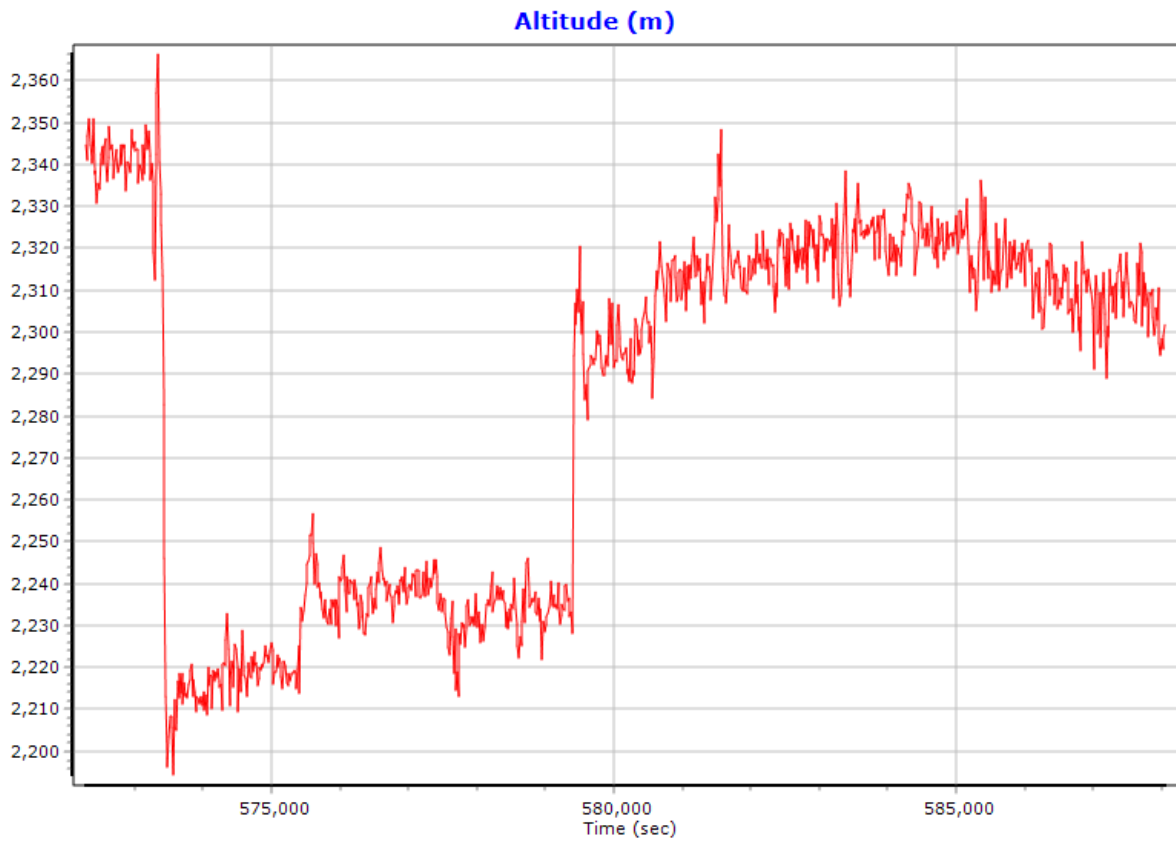
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

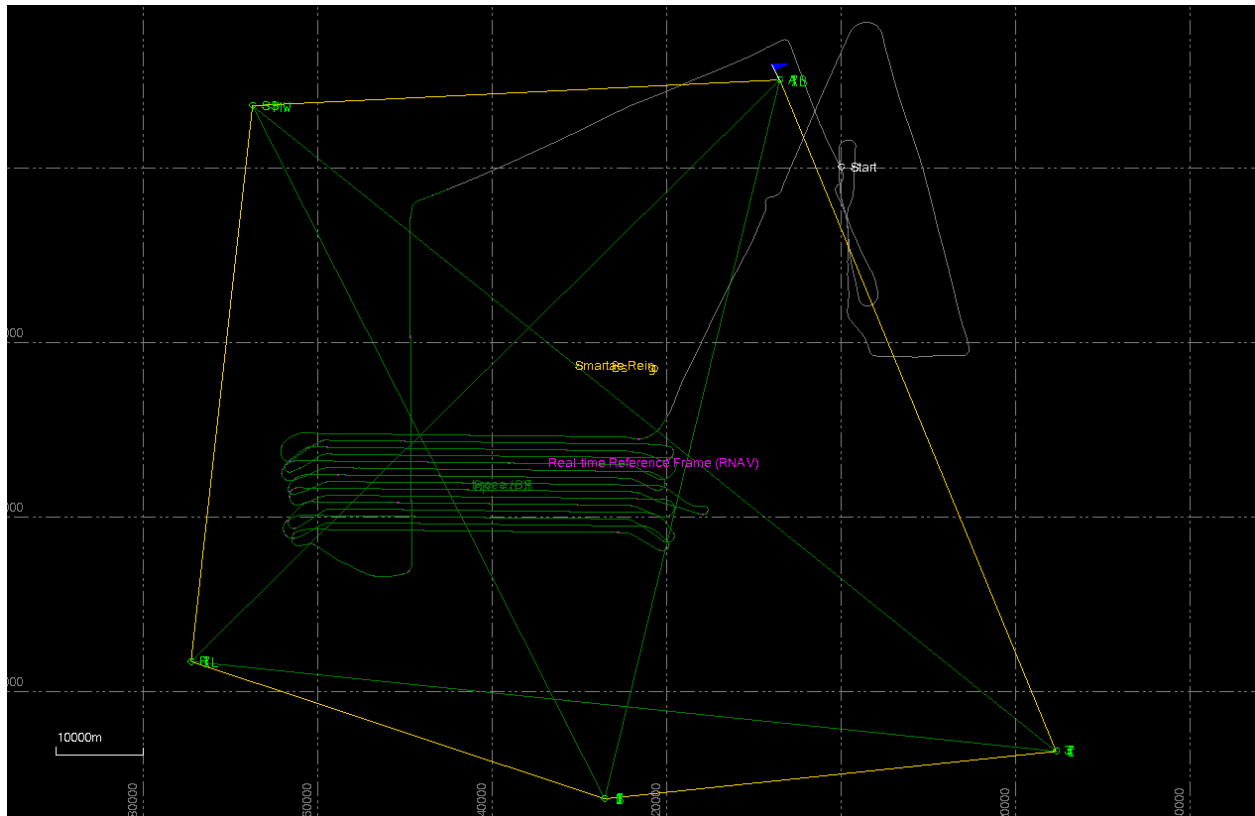
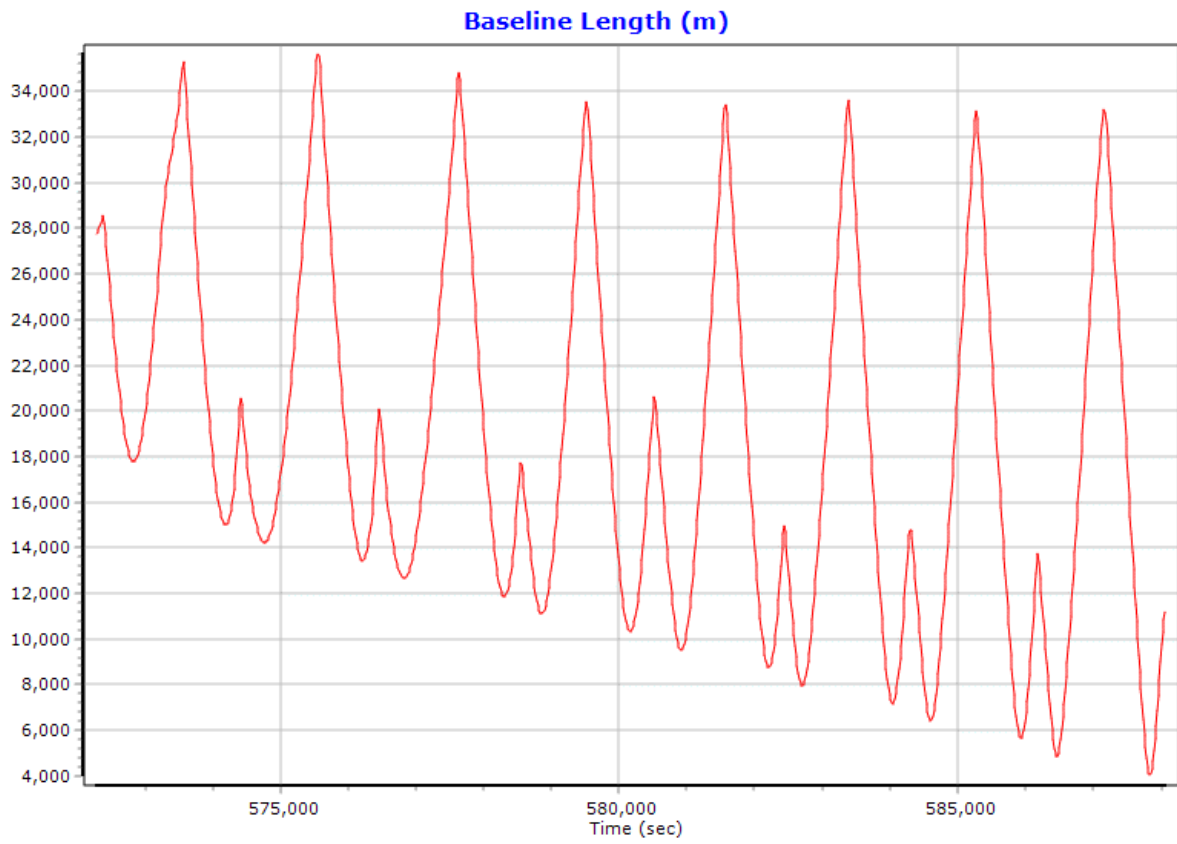
OK Cancel

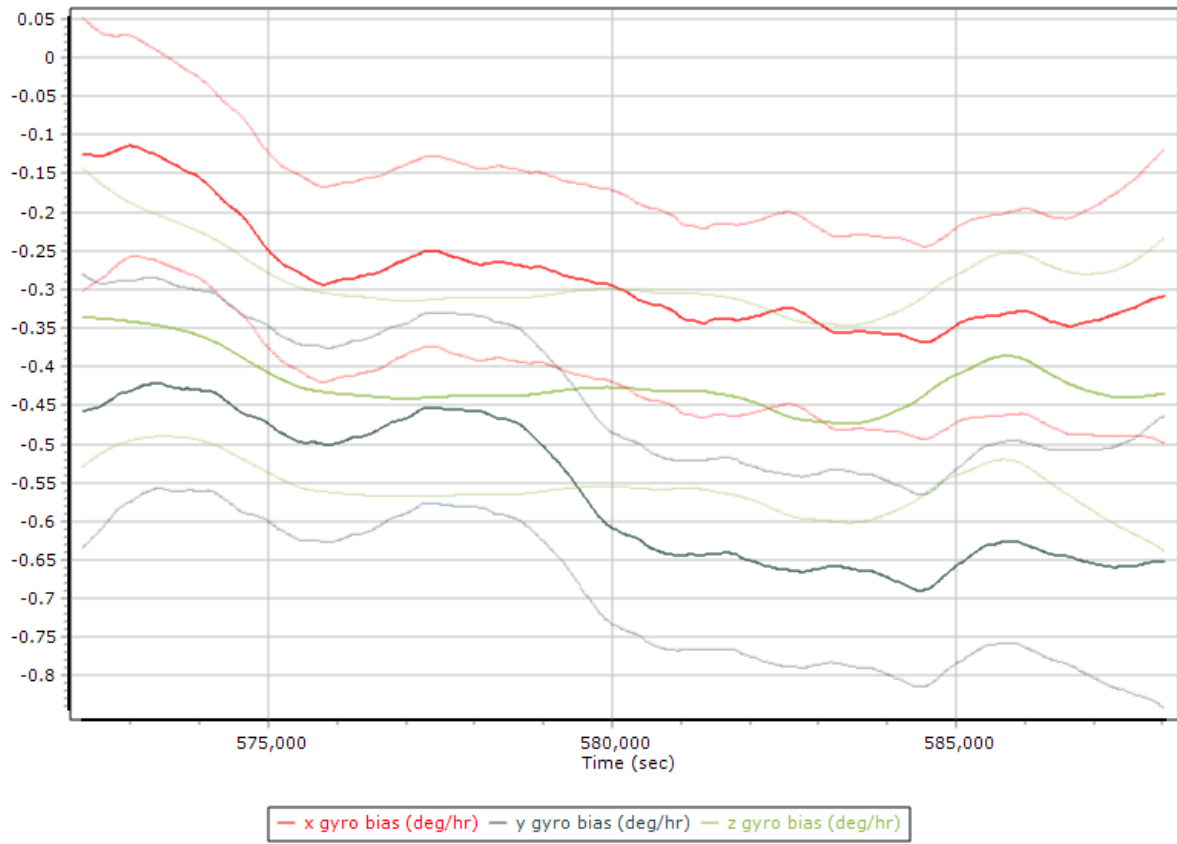
UNB18069A

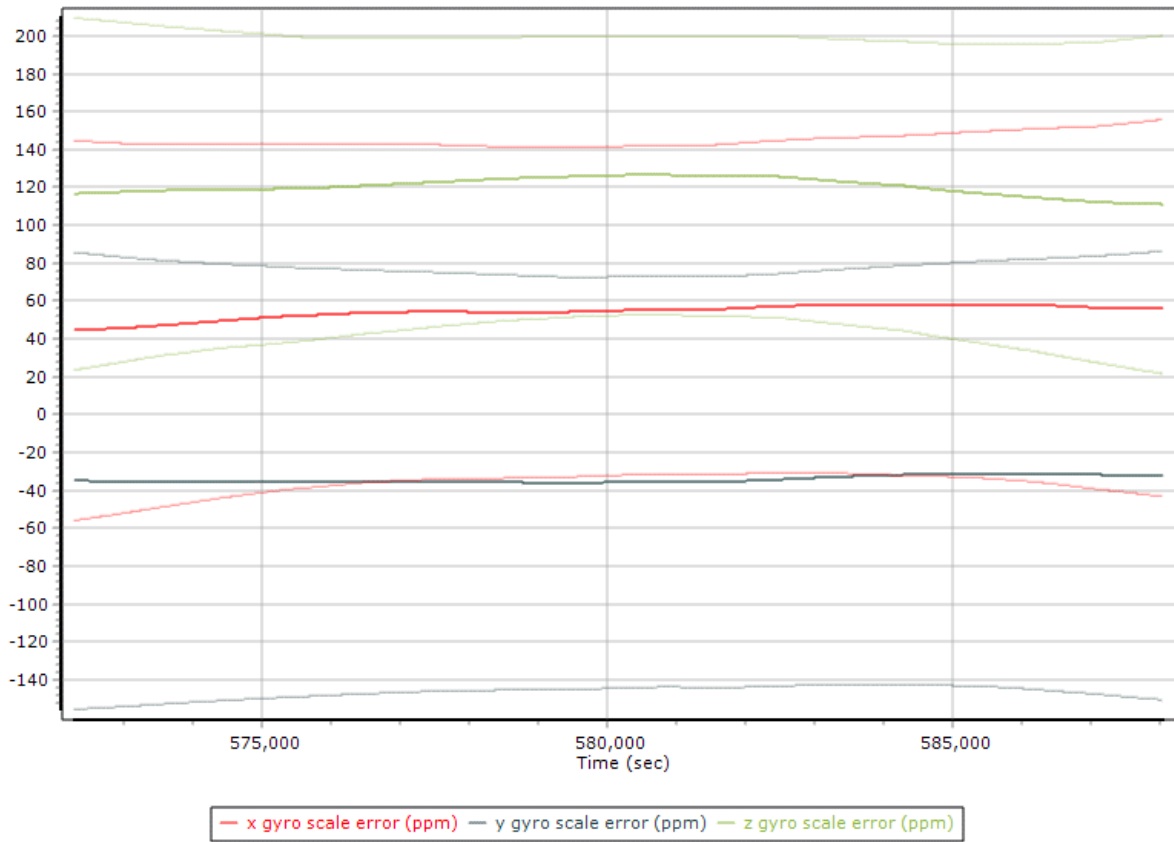












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

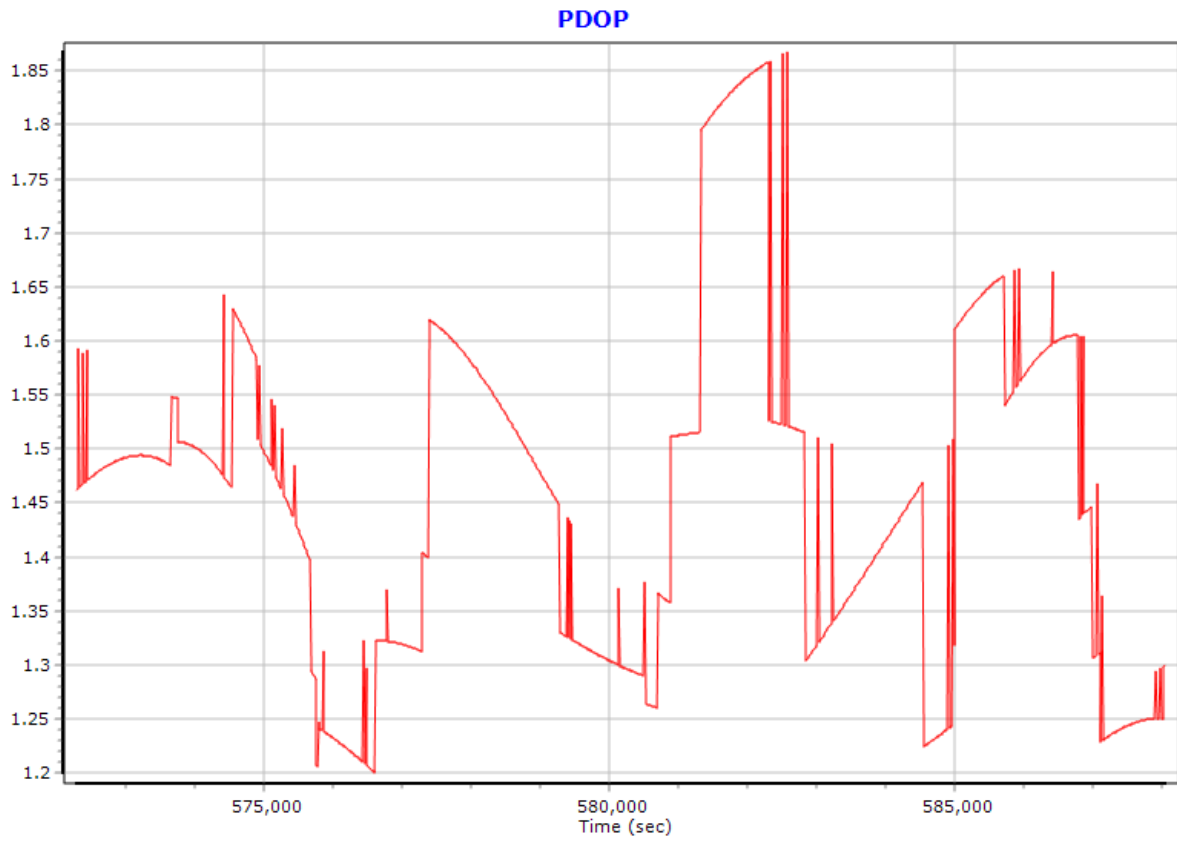
<3cm 10cm 50cm 1m 10m

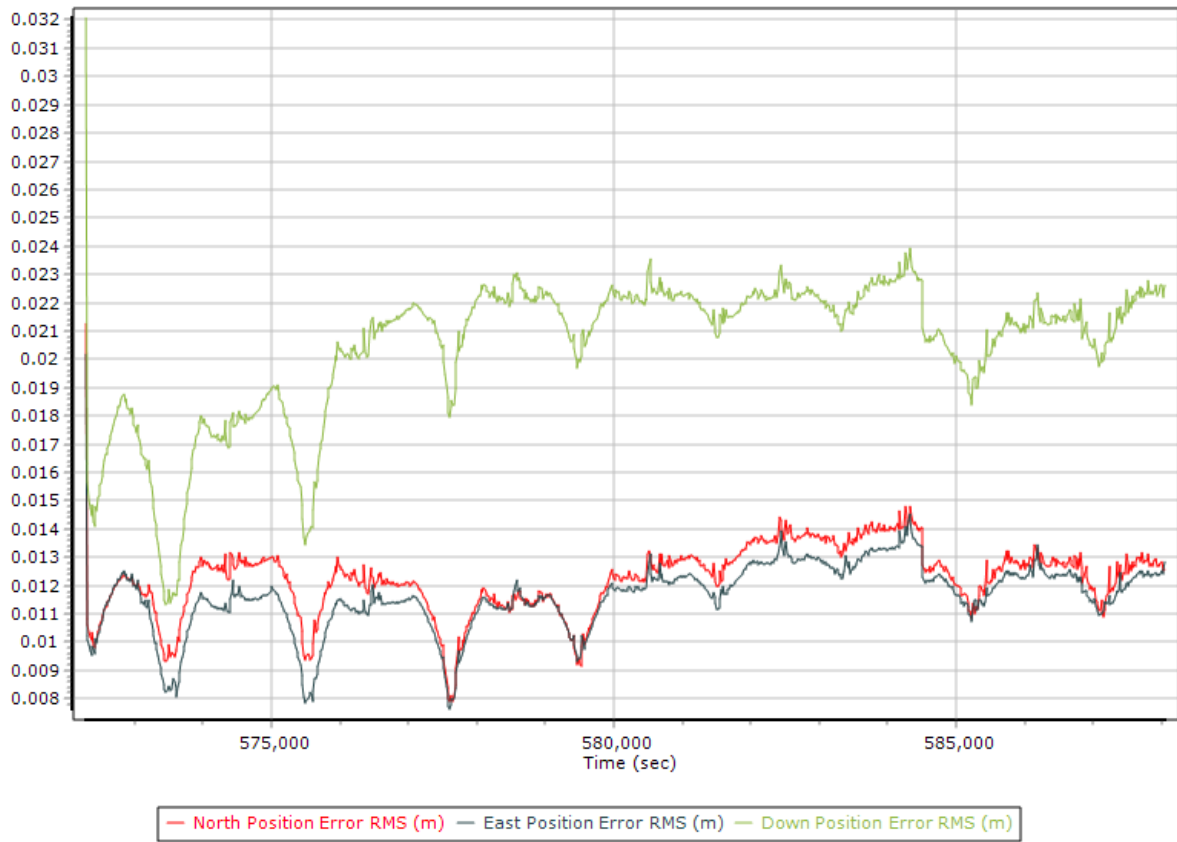
Aircraft to Reference Mounting Angles

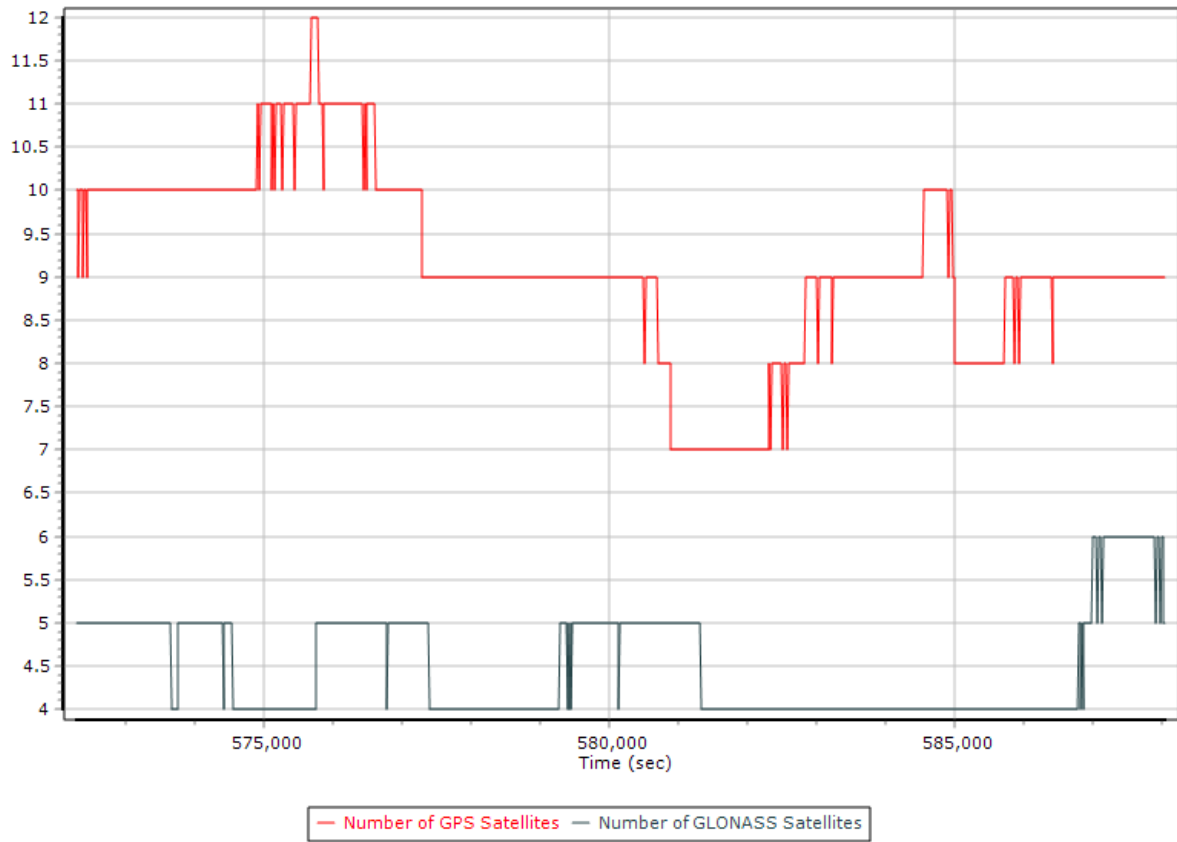
X:

Y:

Z:









Project Settings [X]

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

Timing

Start: 572288.094
 End: 588078.704

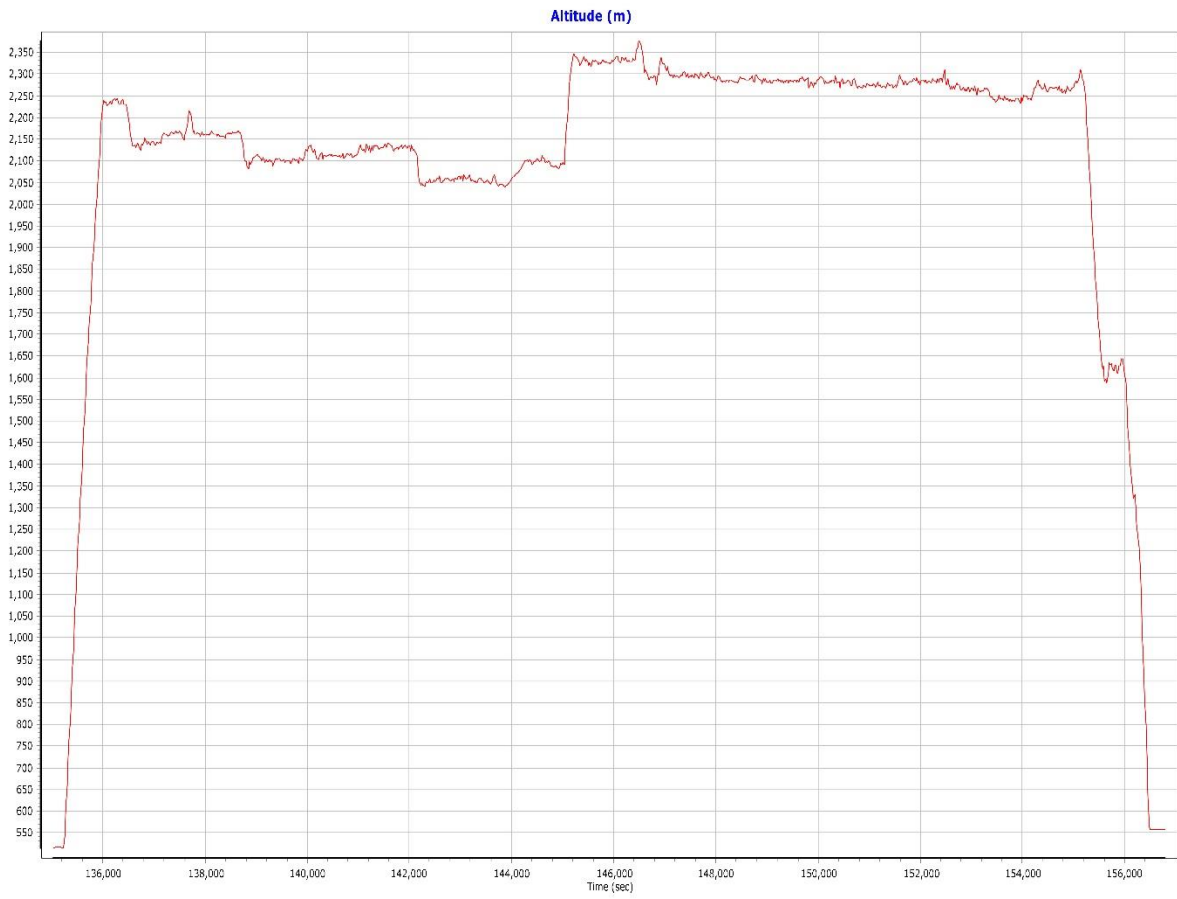
Entire time interval
 Seconds of start week

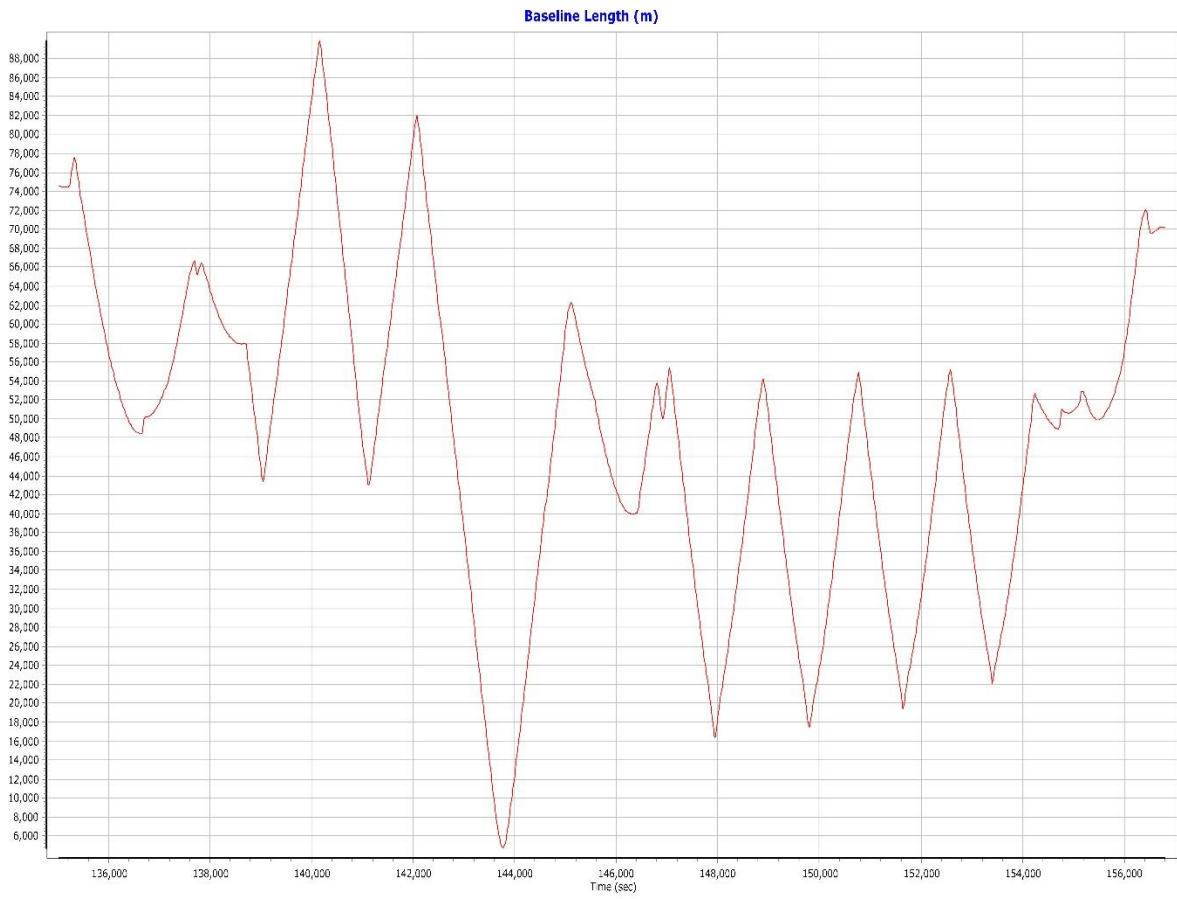
UTC Offset: 18.000

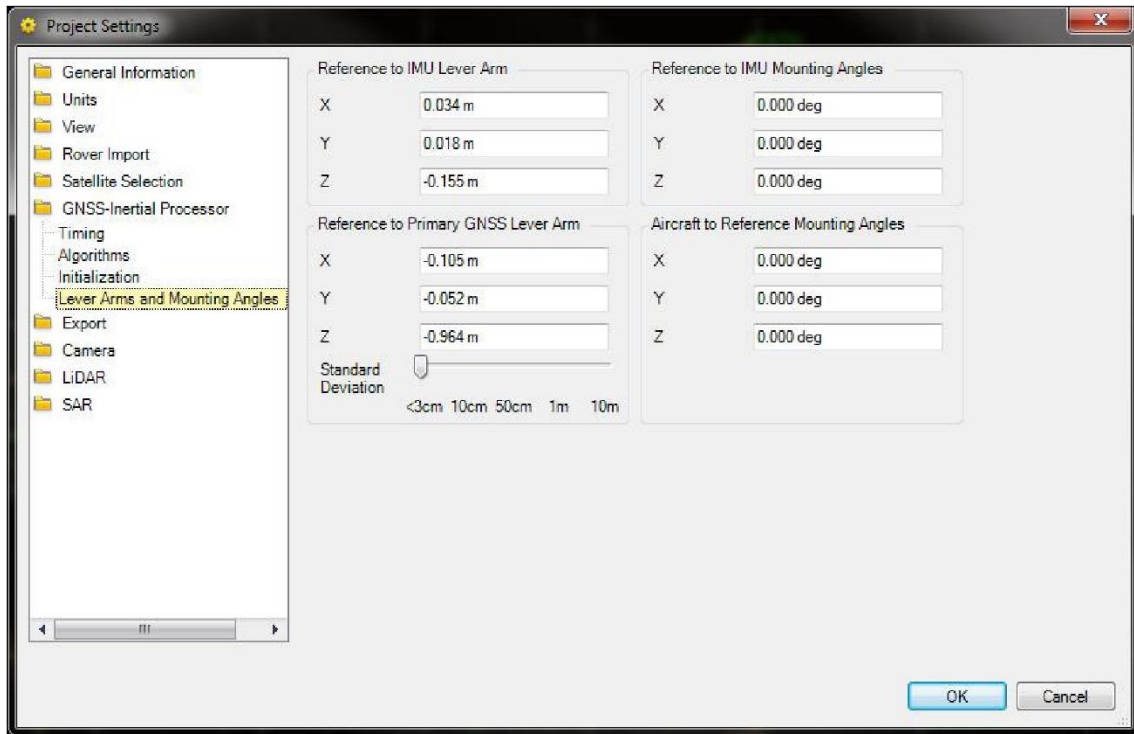
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

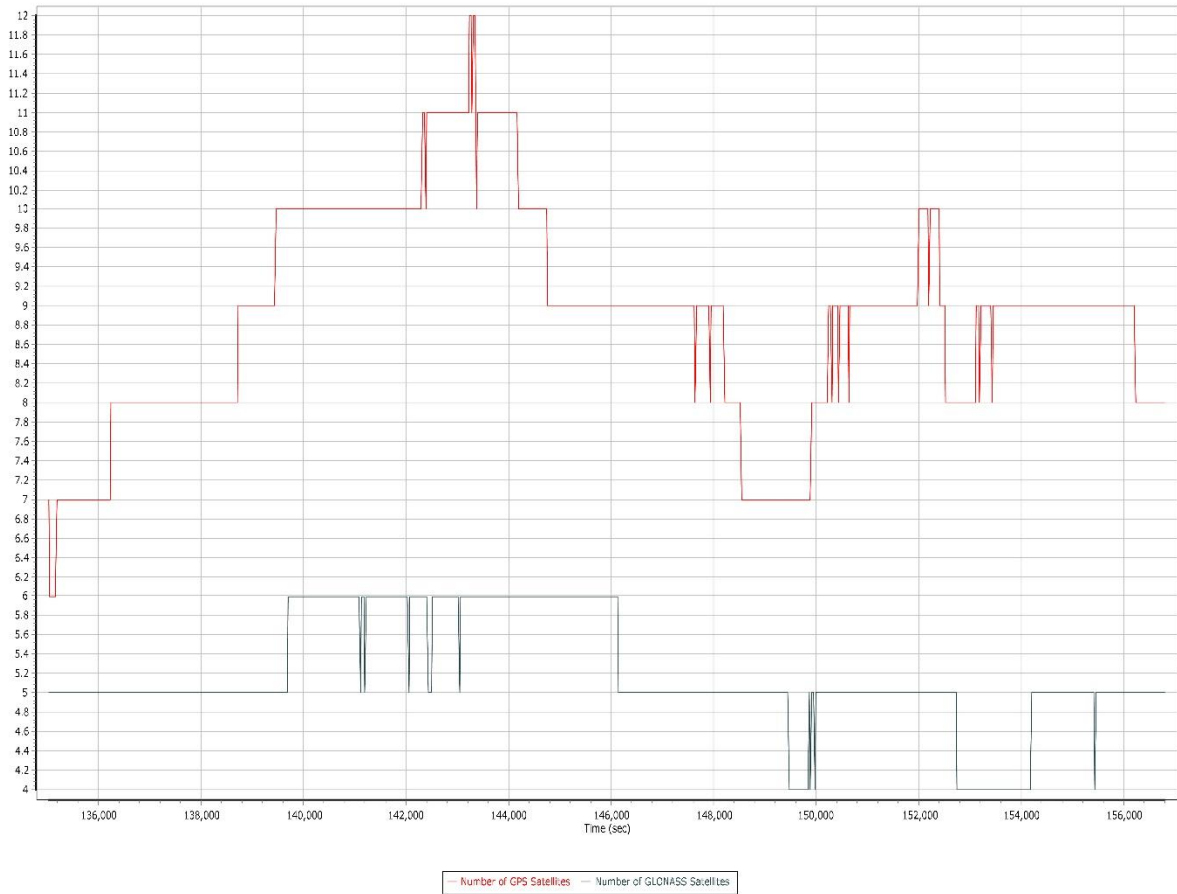
OK Cancel

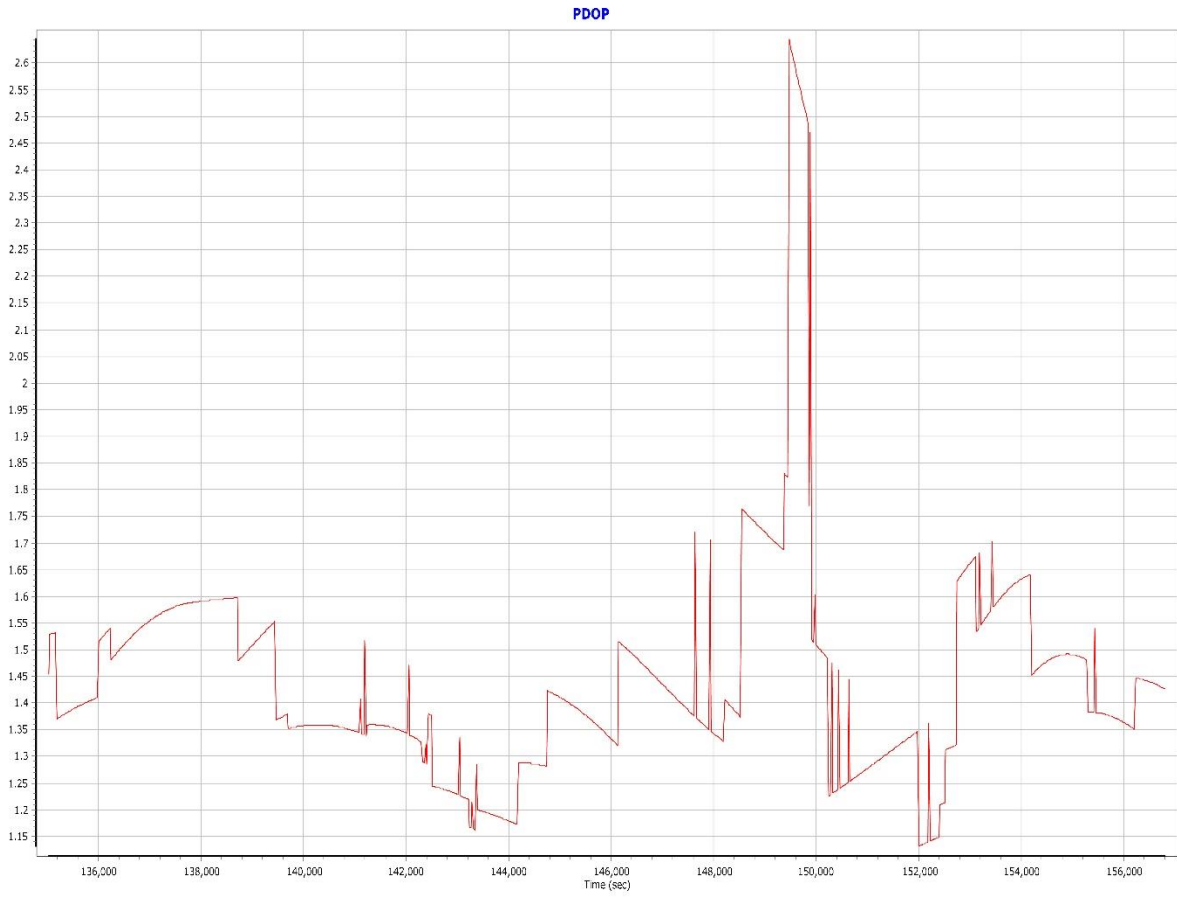
UNB18071A

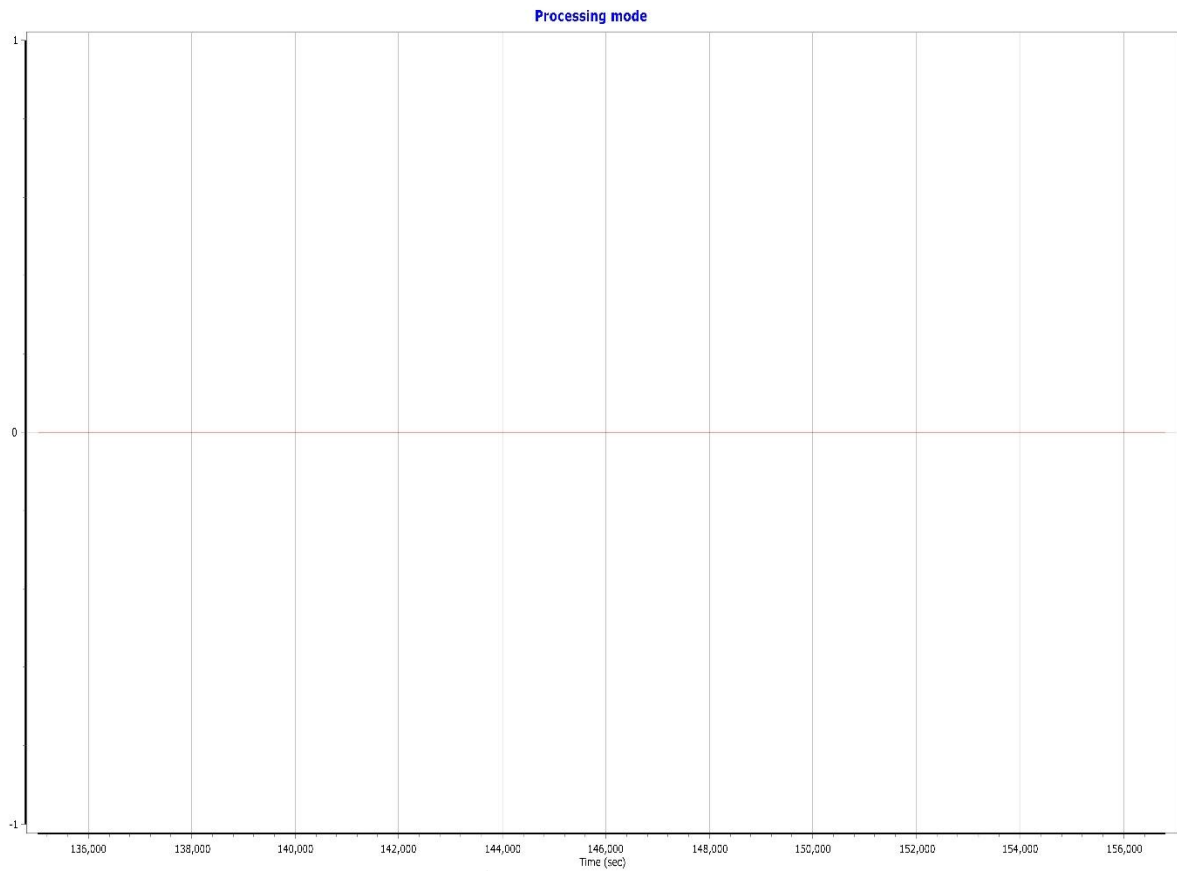






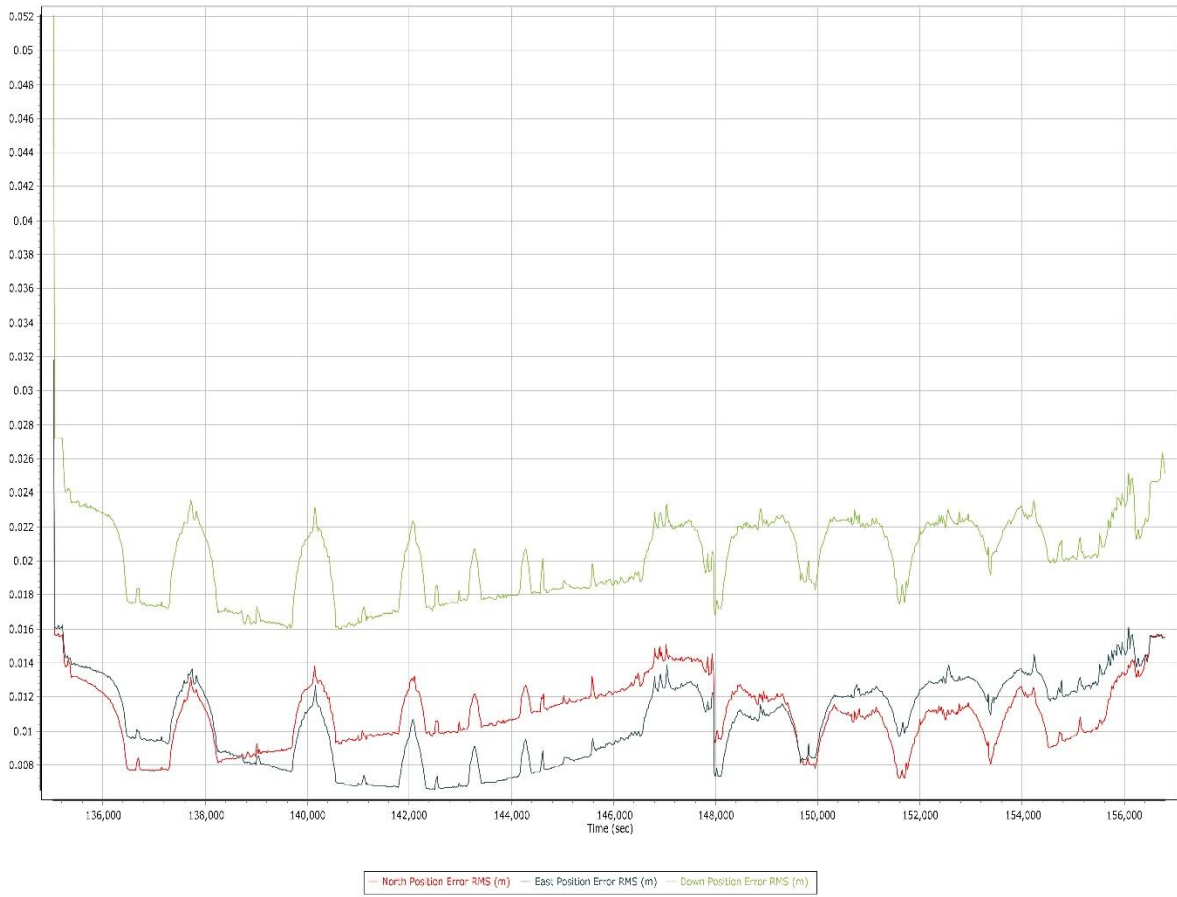


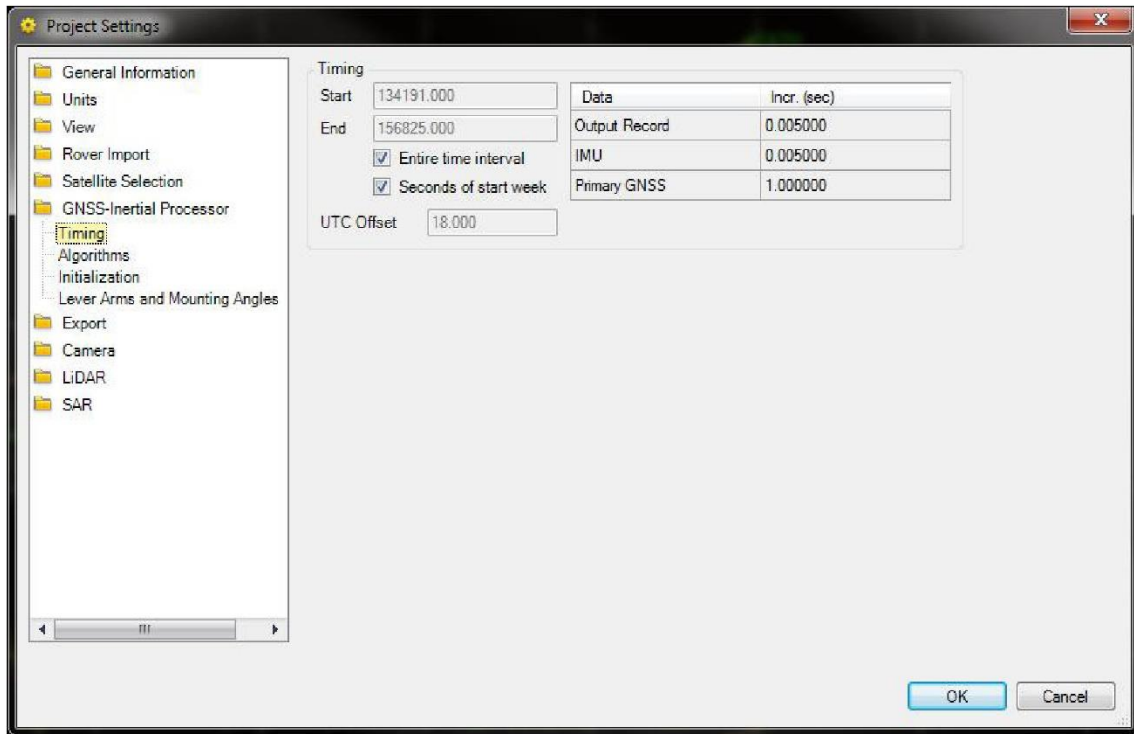


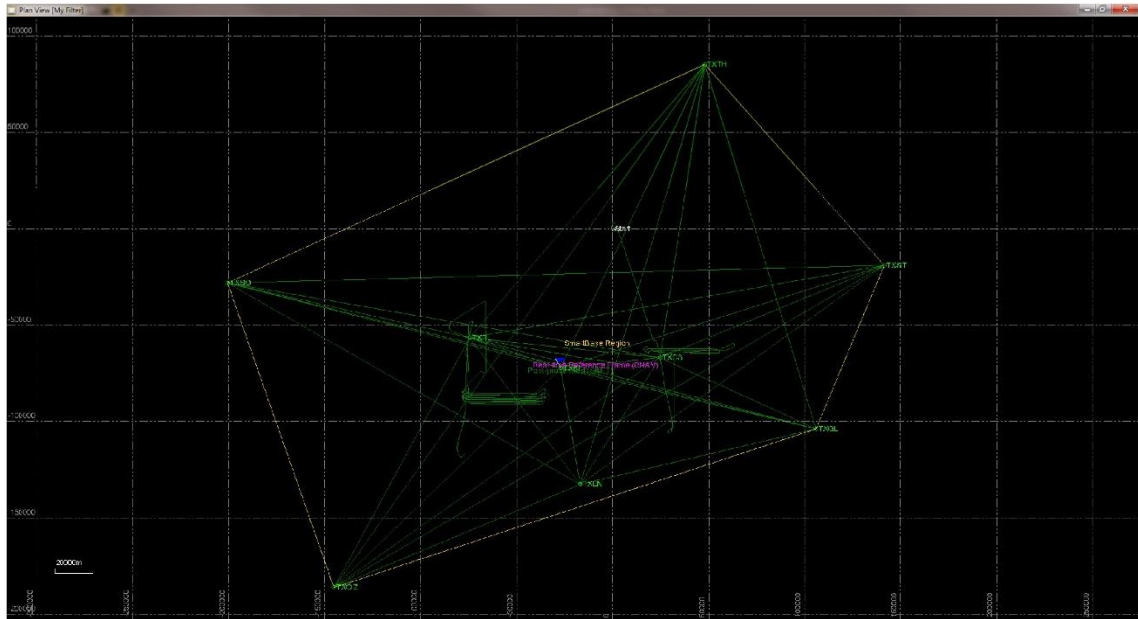


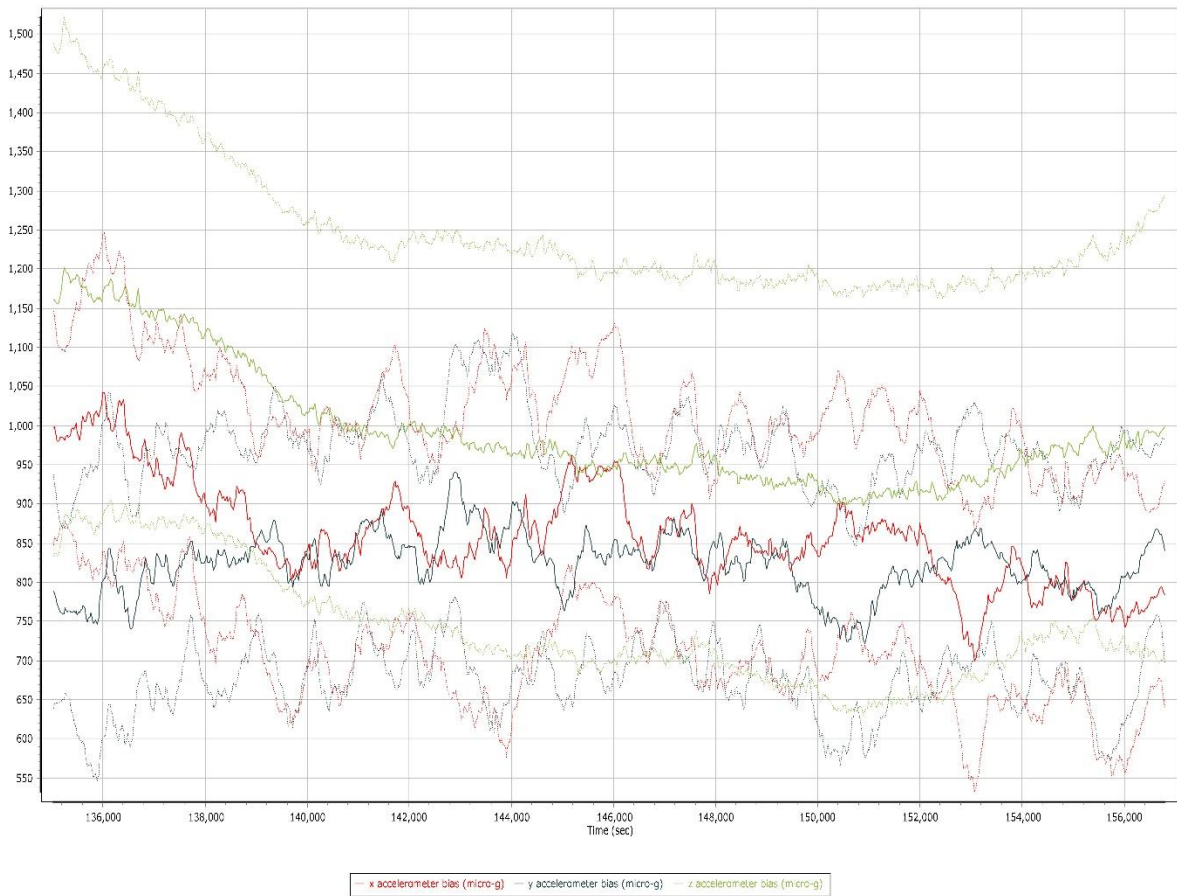
0 = Fixed NL, 1 = fixed WL, 2 = float, 3 = DGNSS, 4 = RTCM, 5 = IA PPP, 6 = C/A, 7 = GNSS Nav, 8 = DR

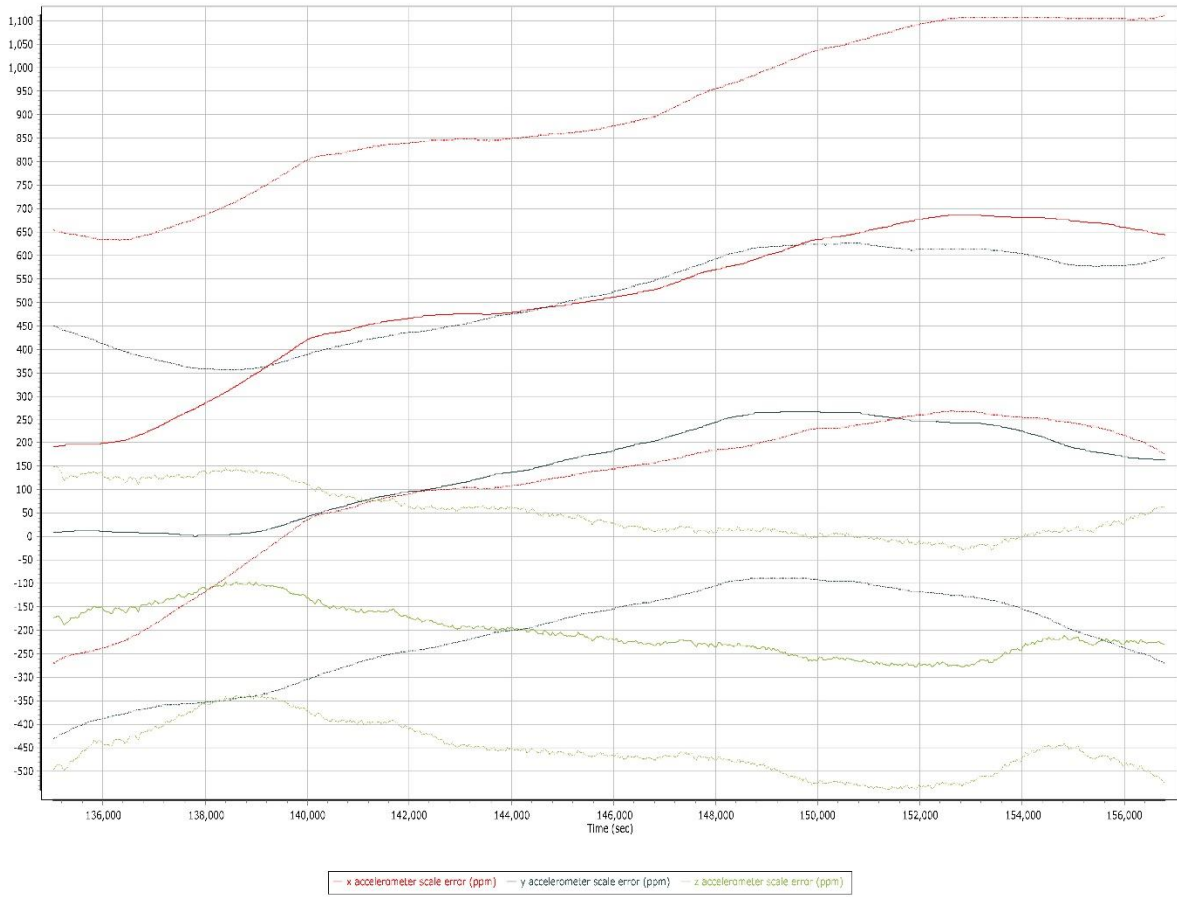


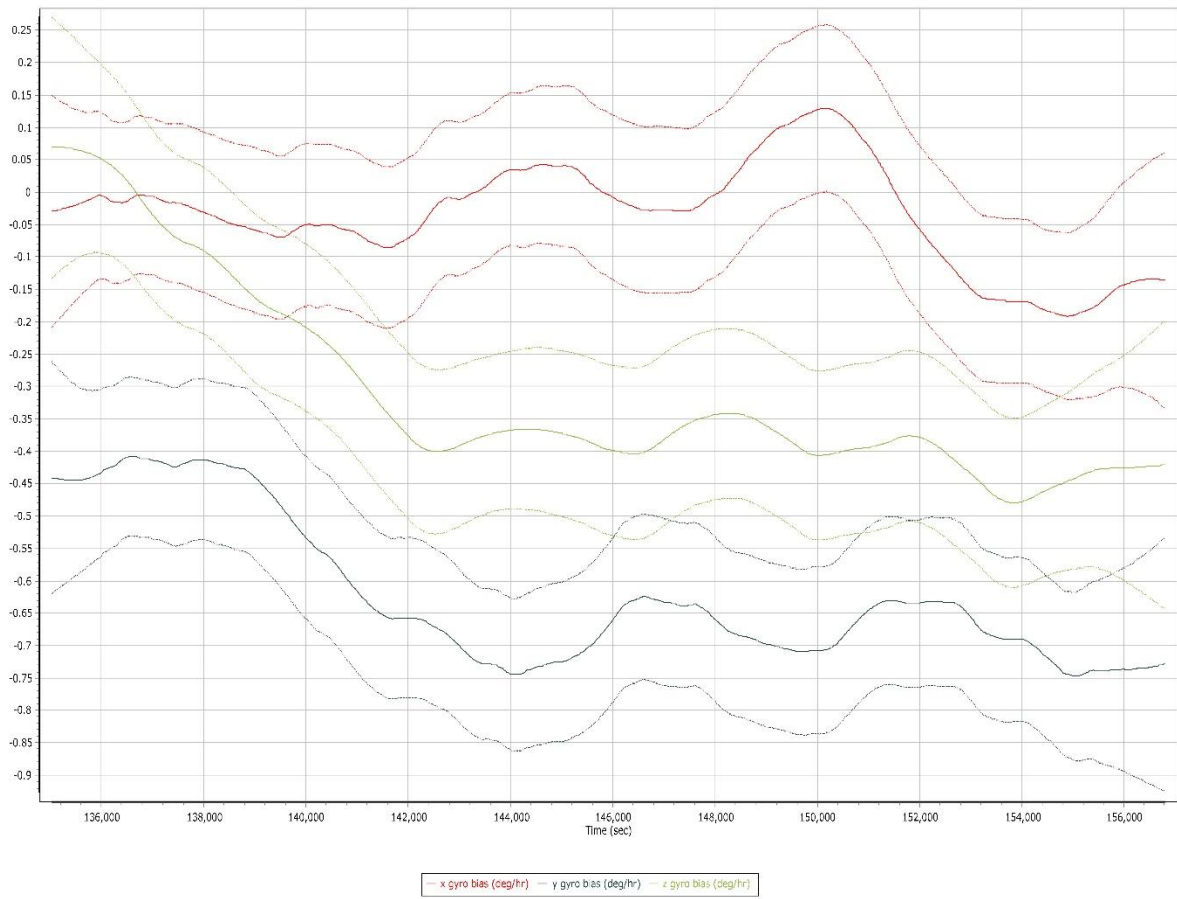


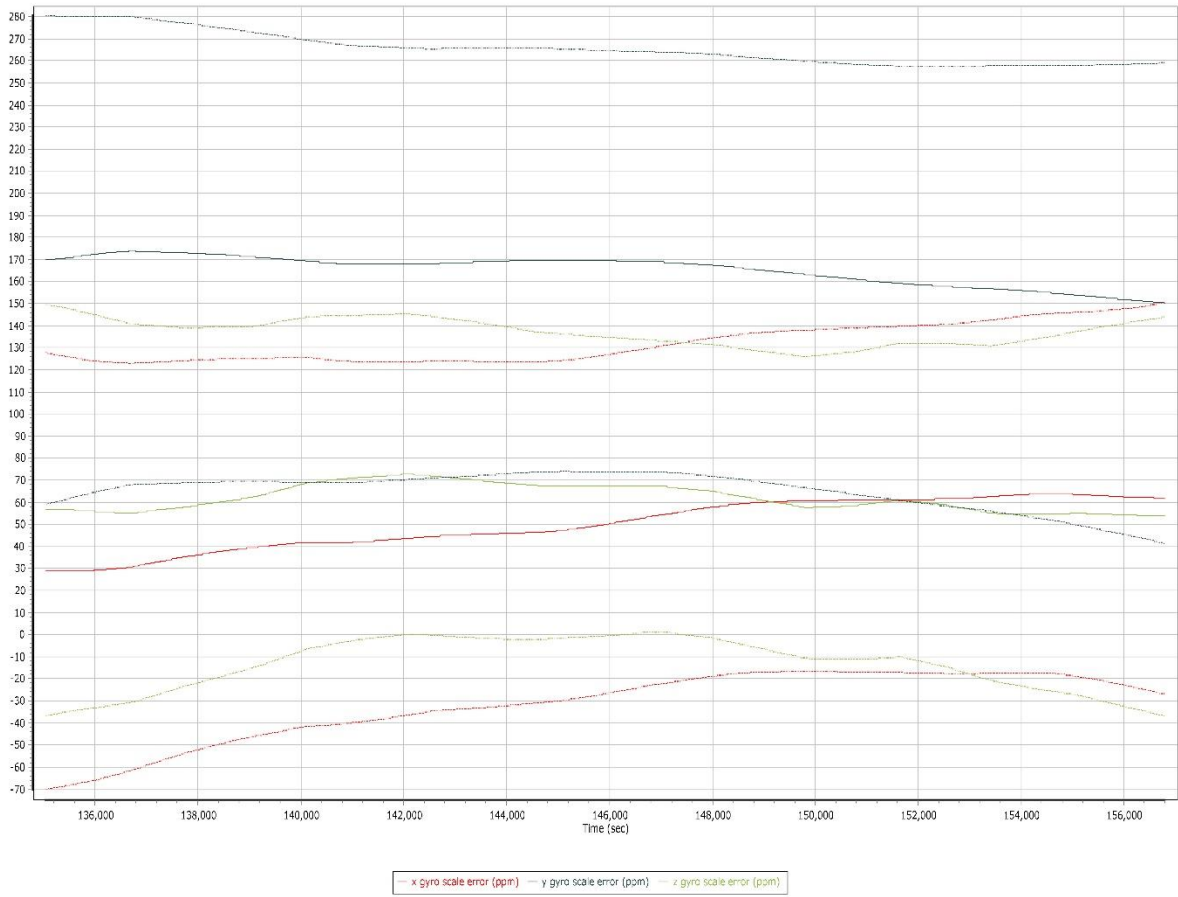




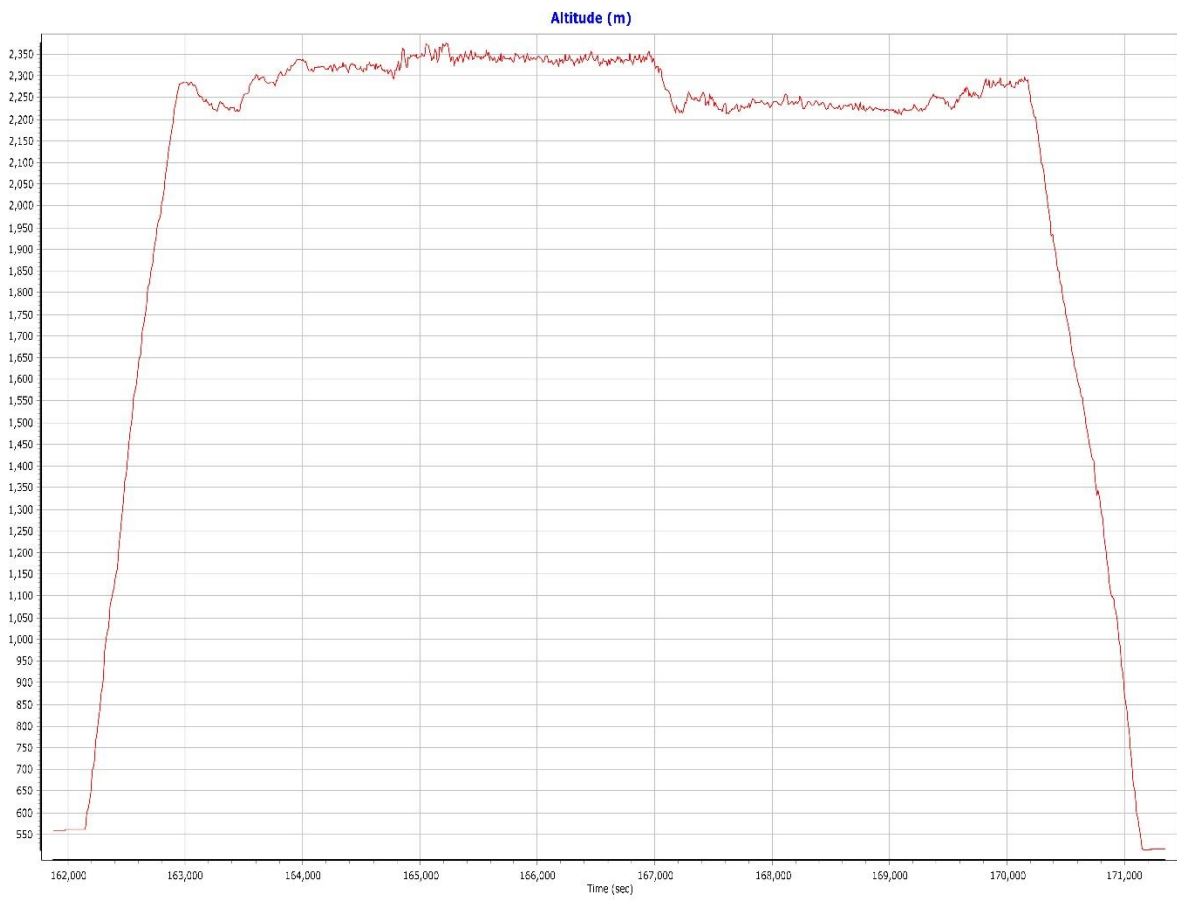


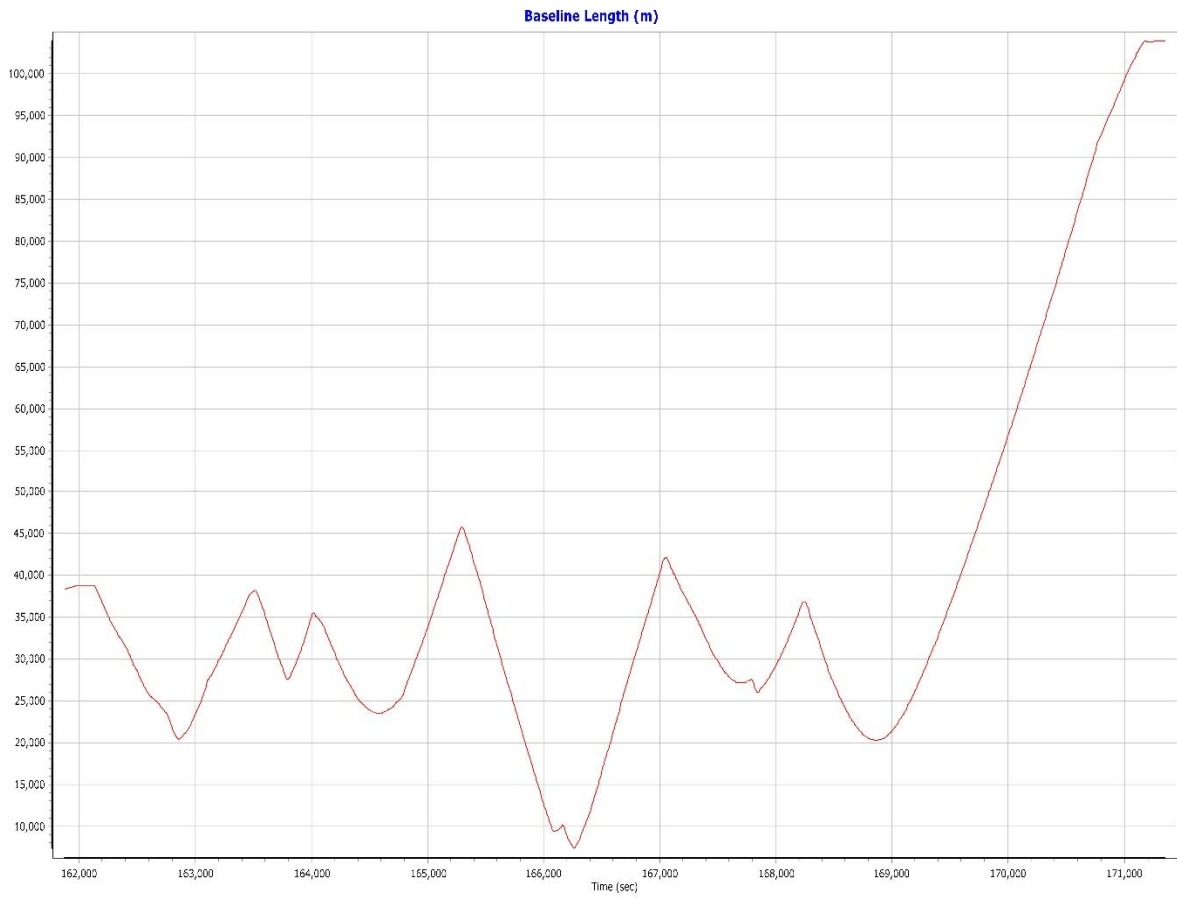


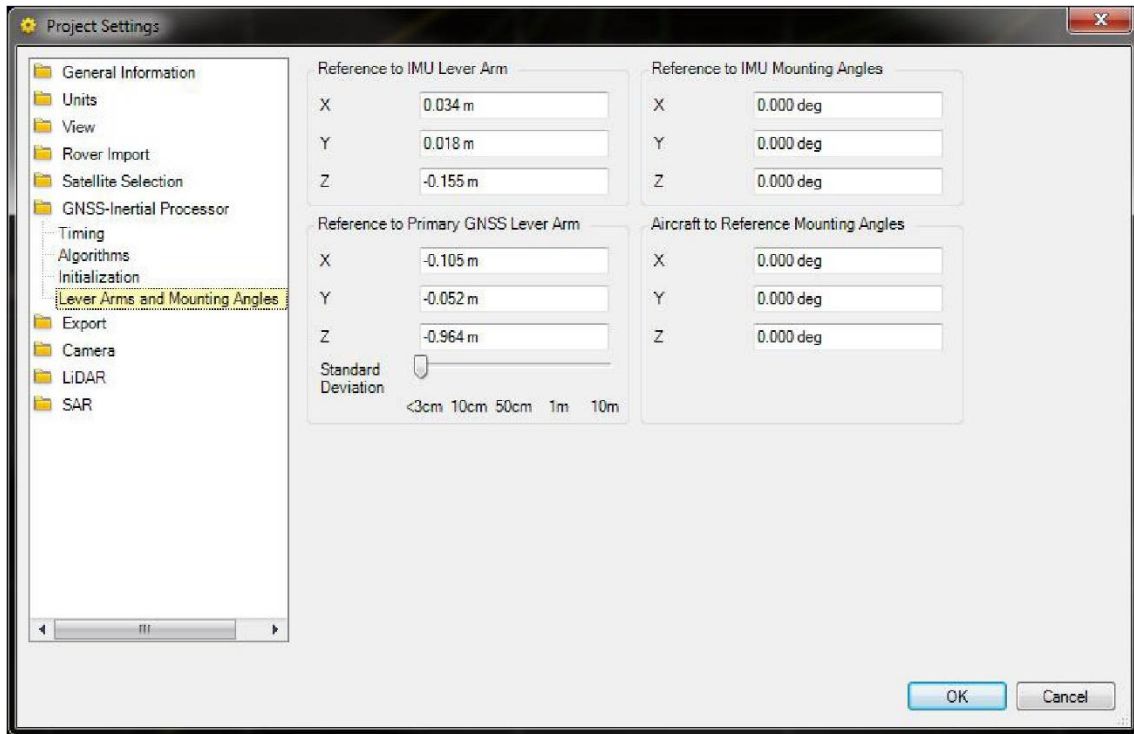


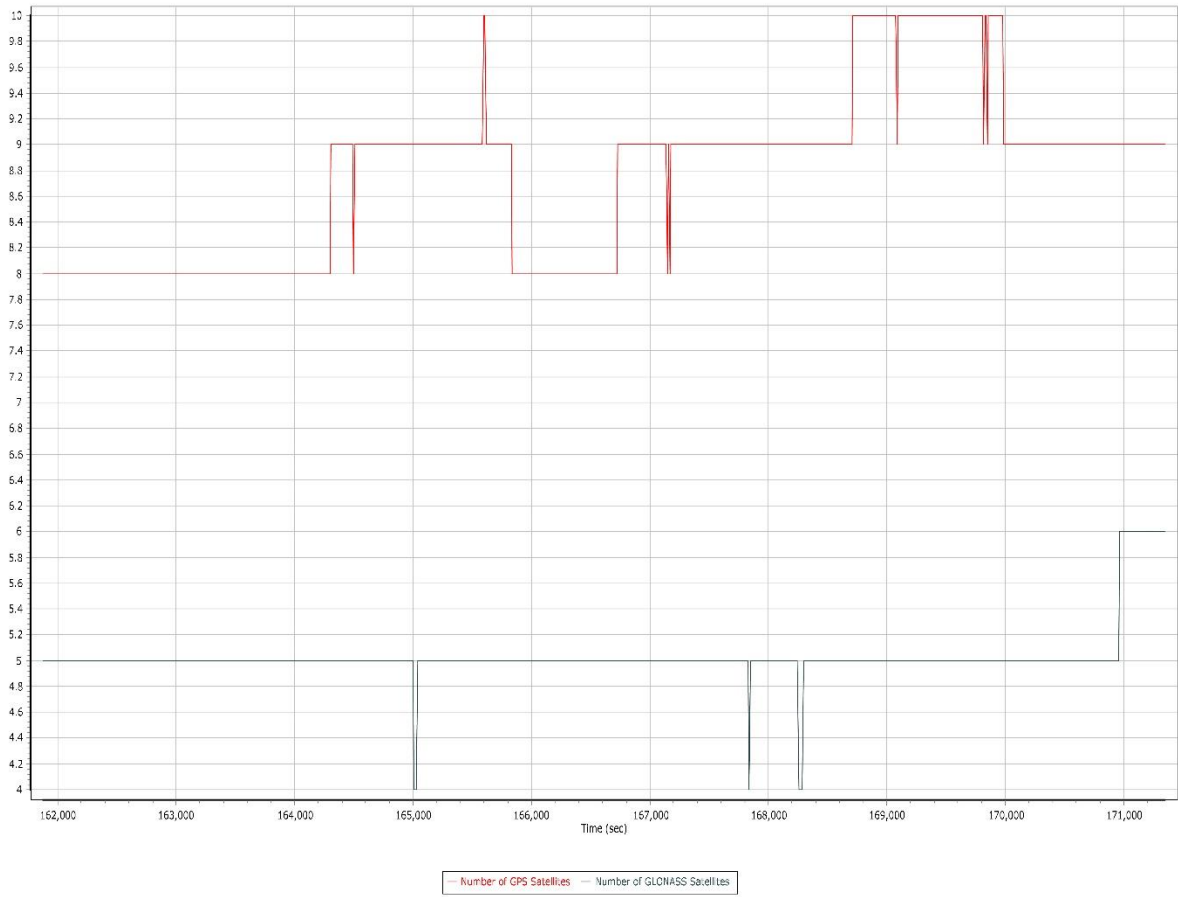


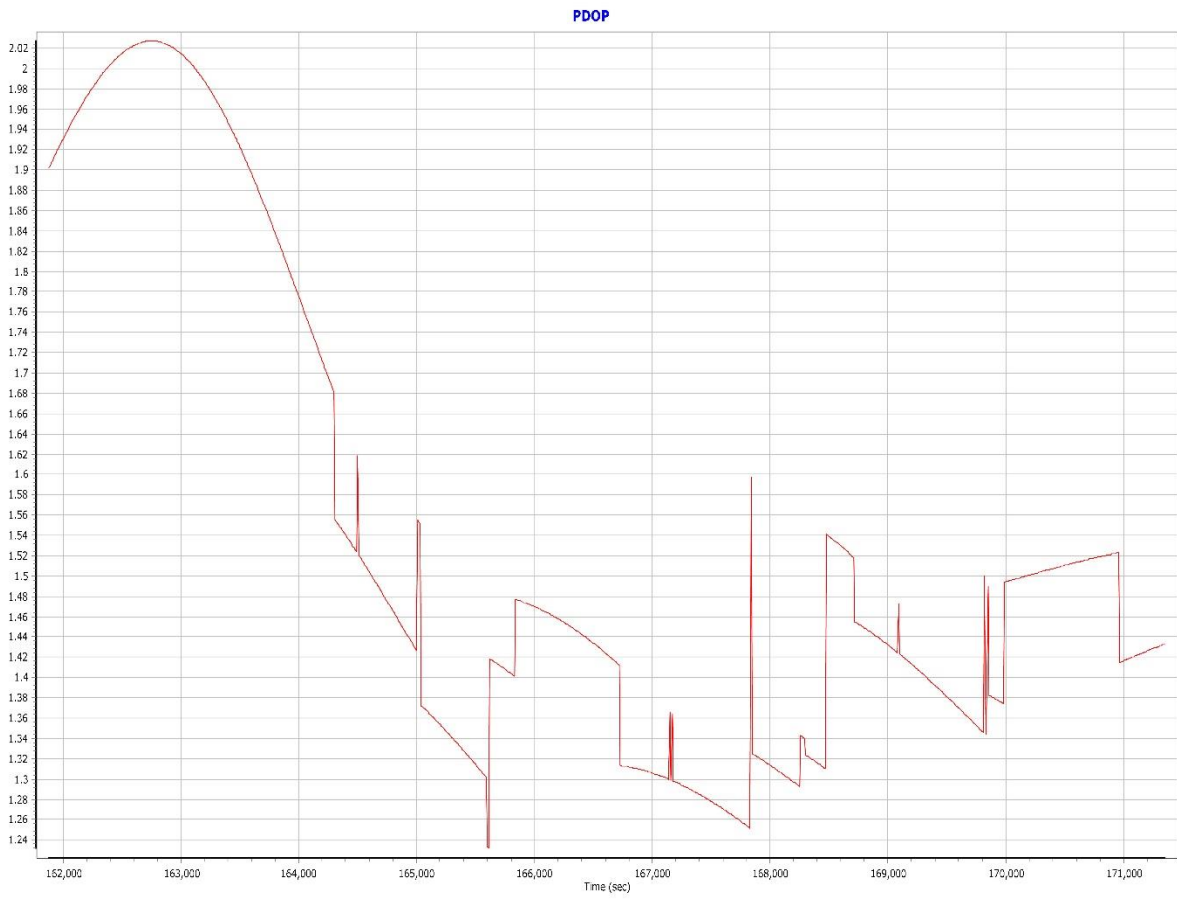
UNB18071B

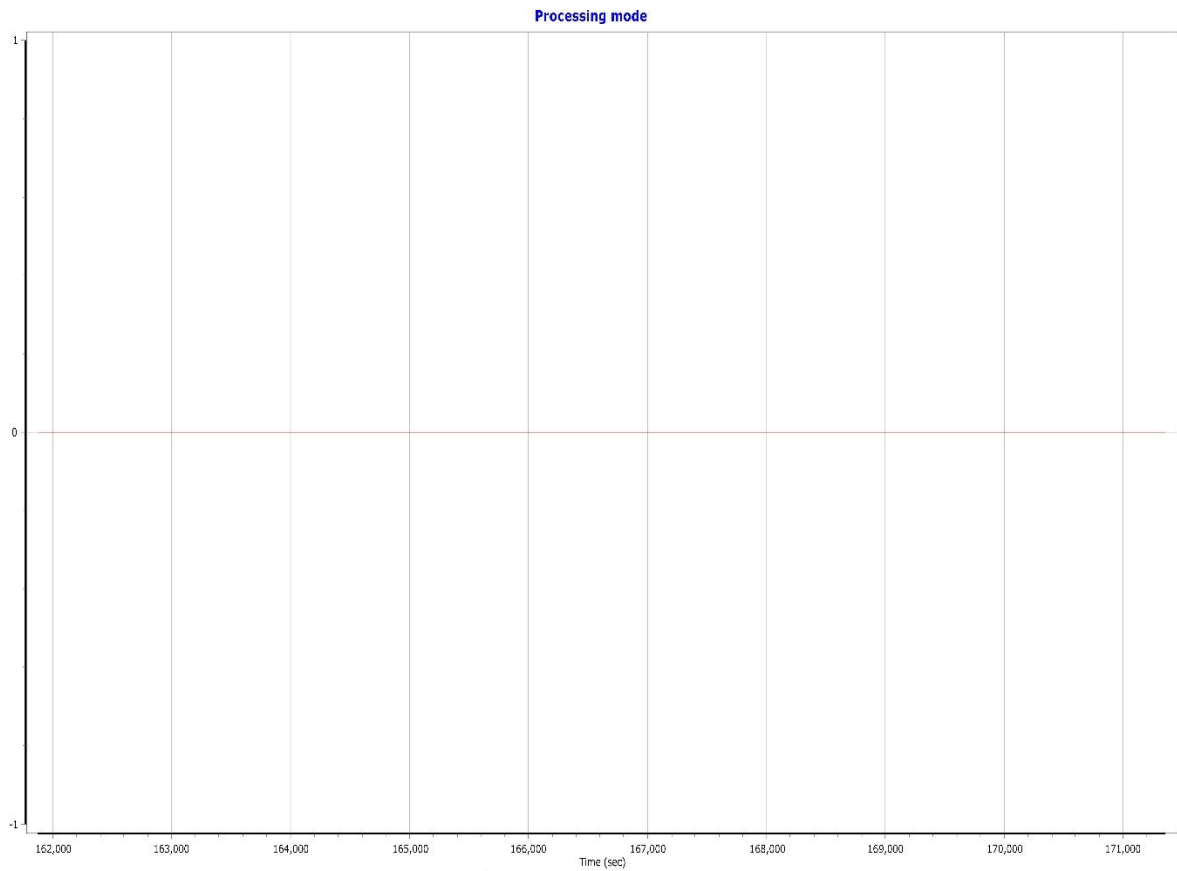


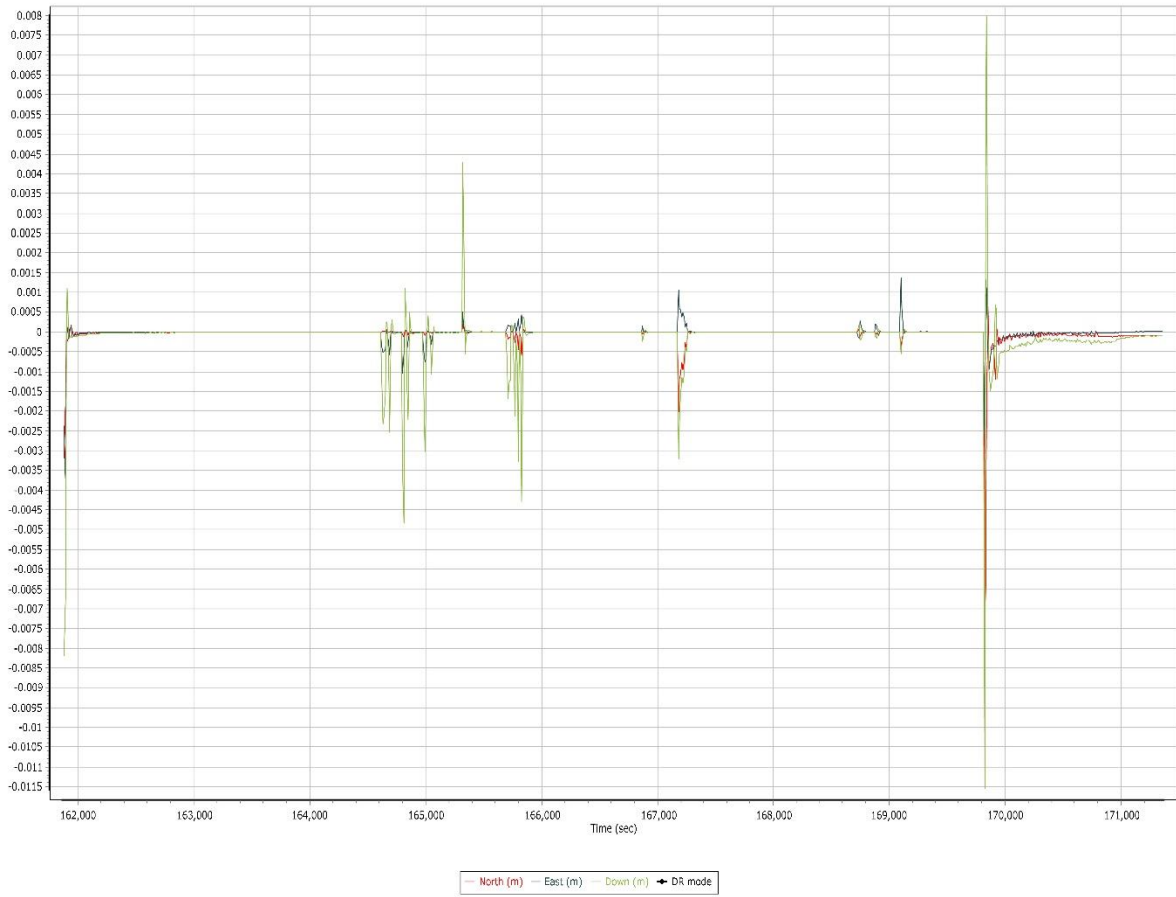




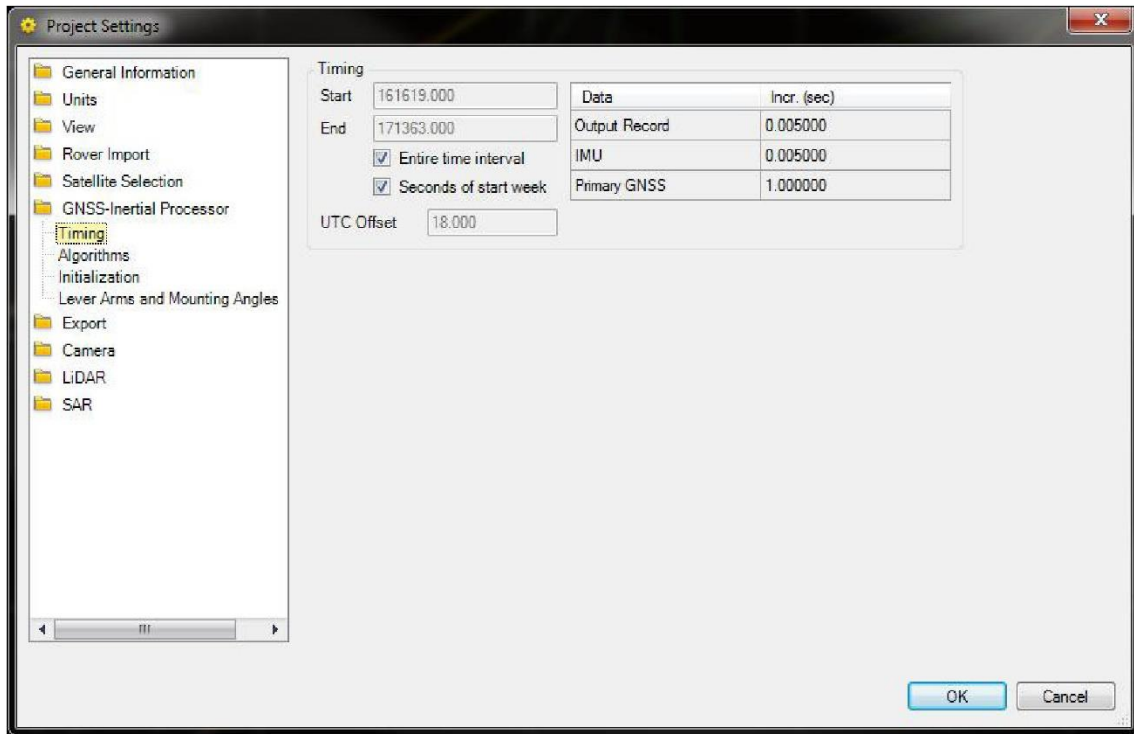


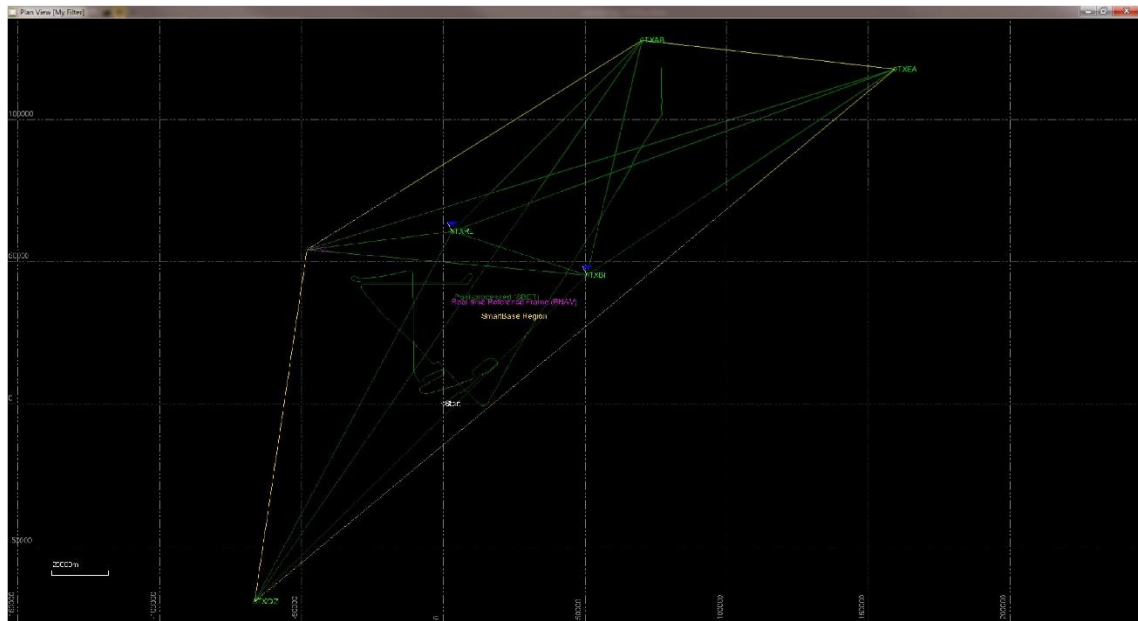




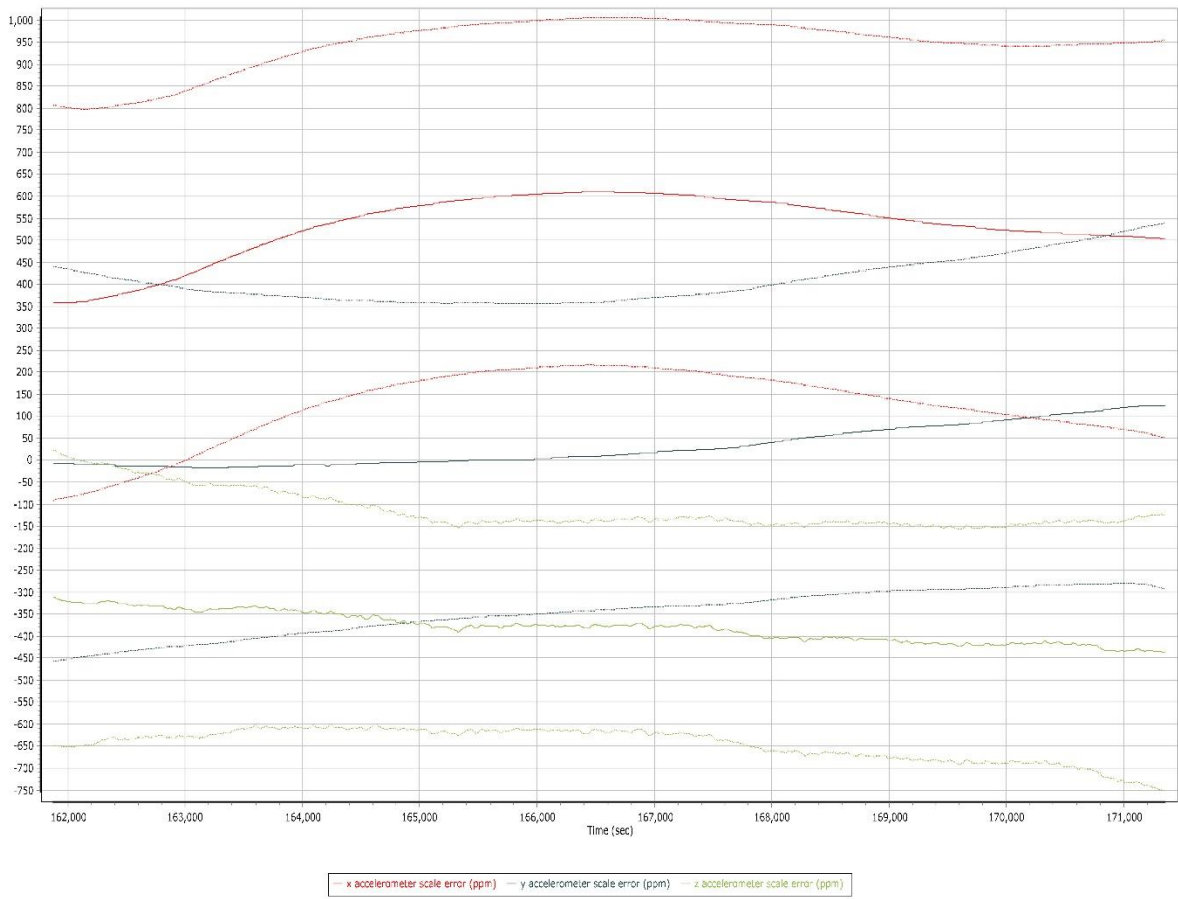


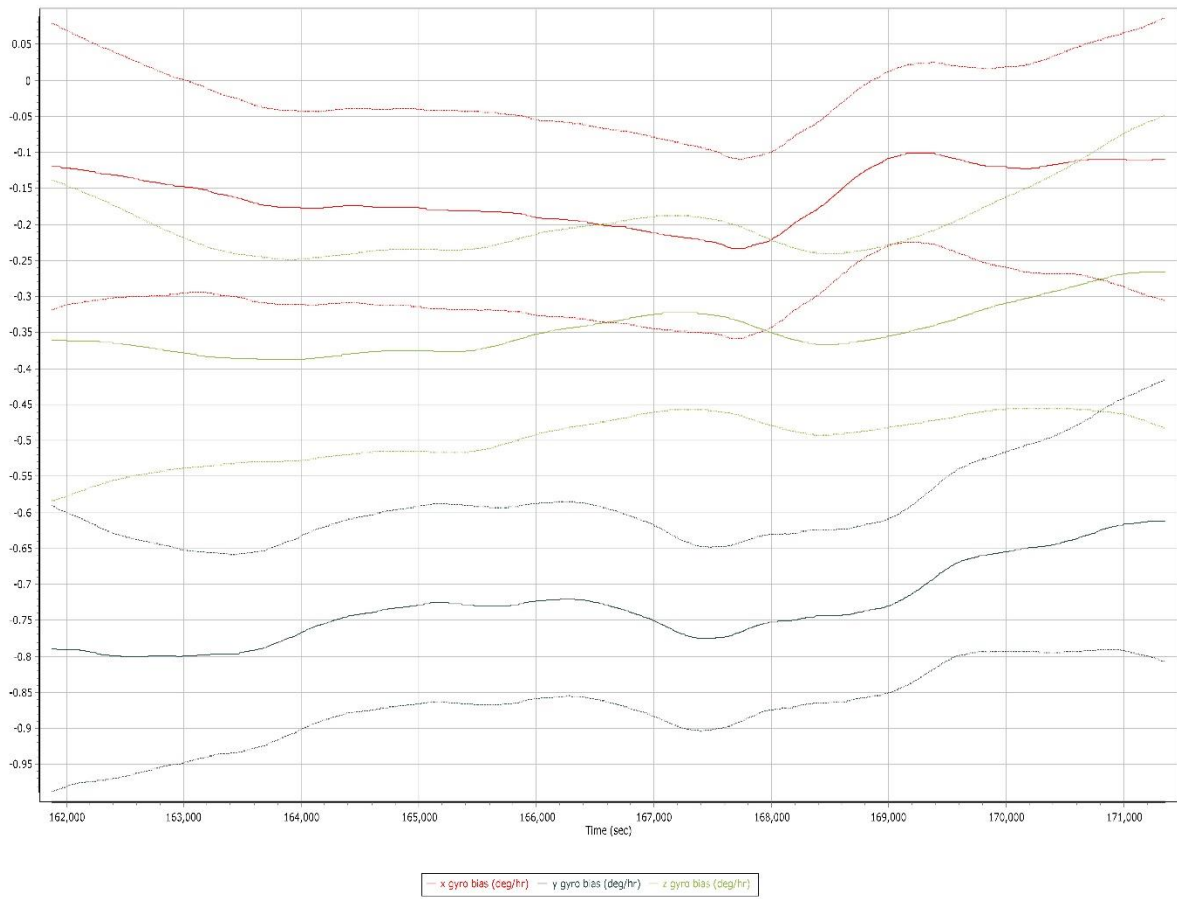


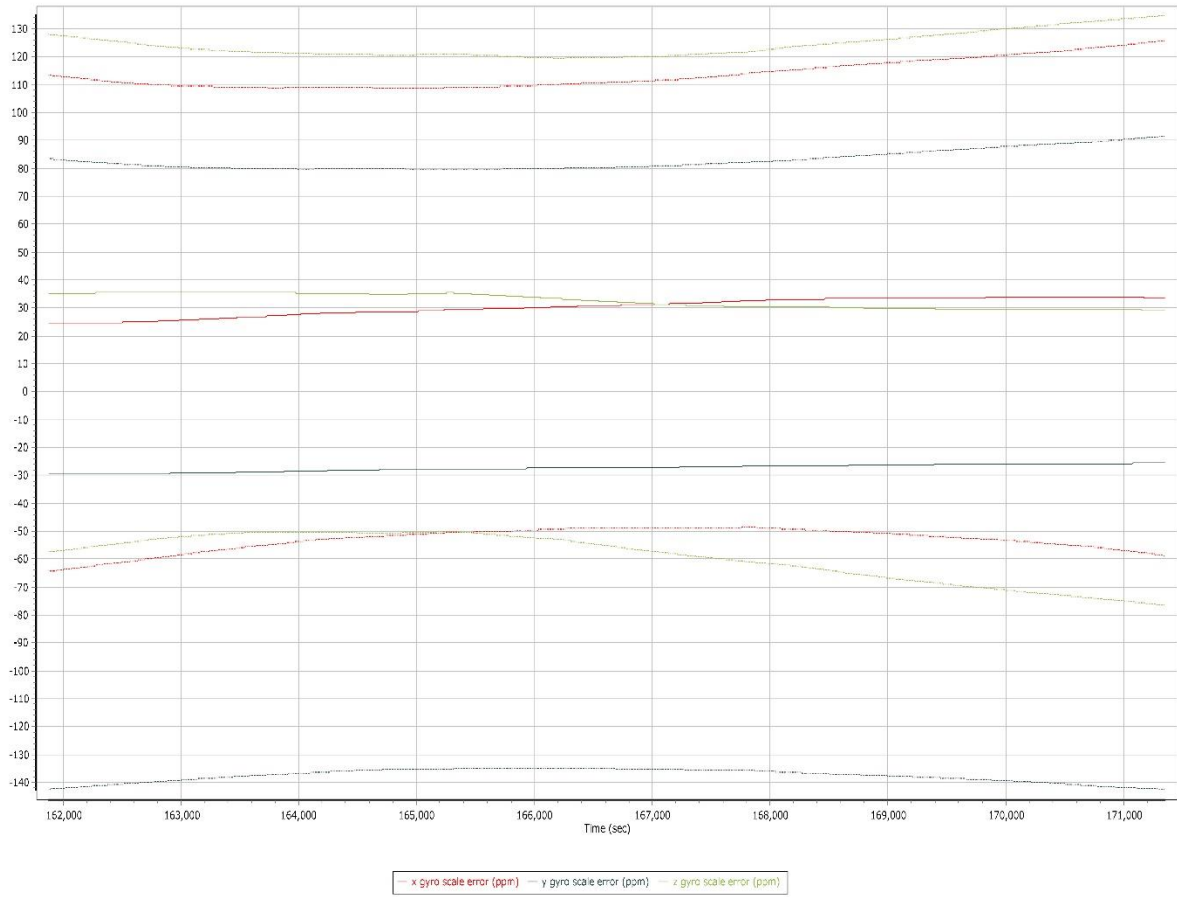




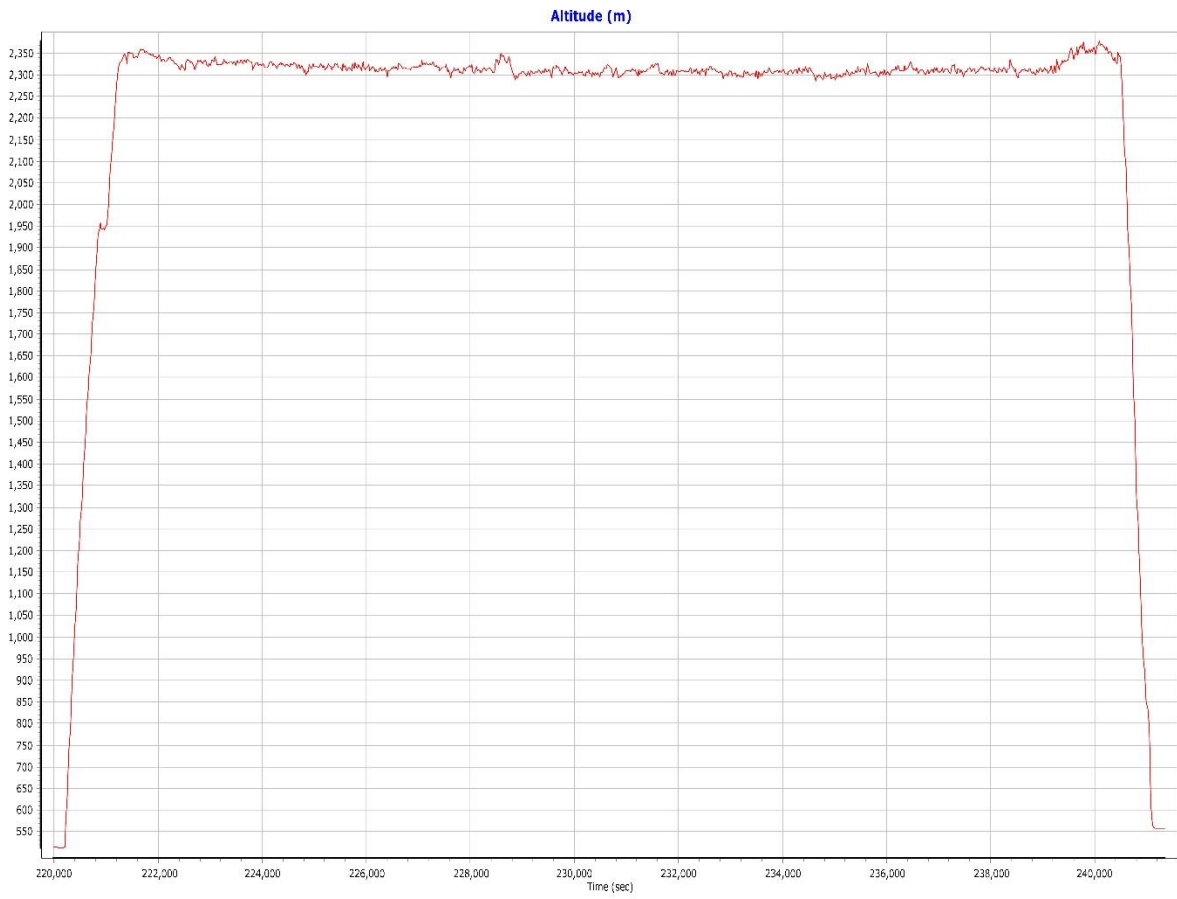


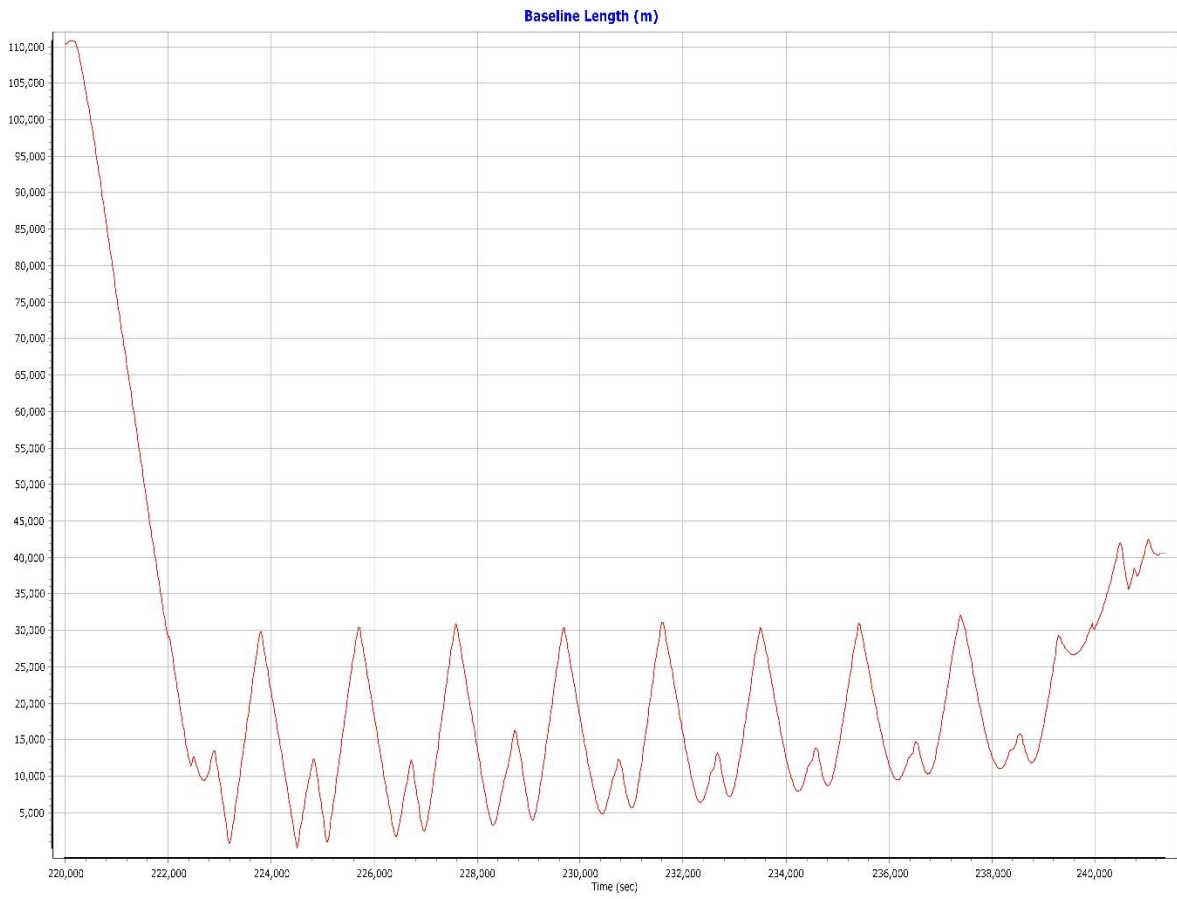


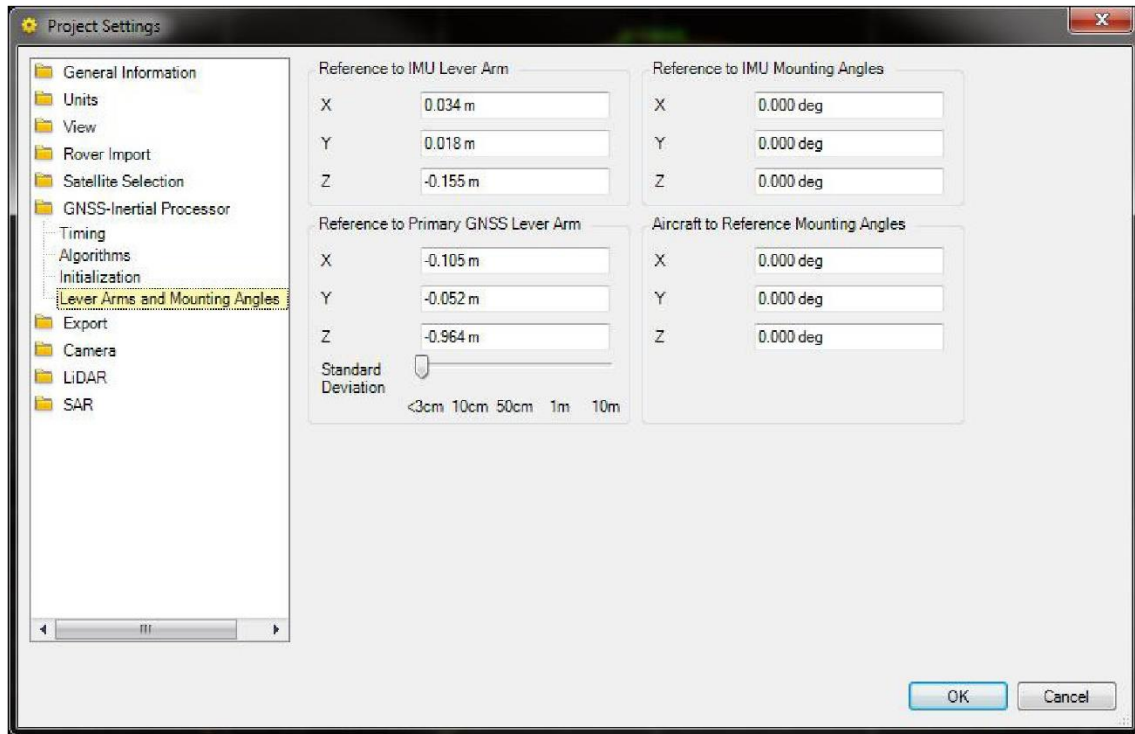


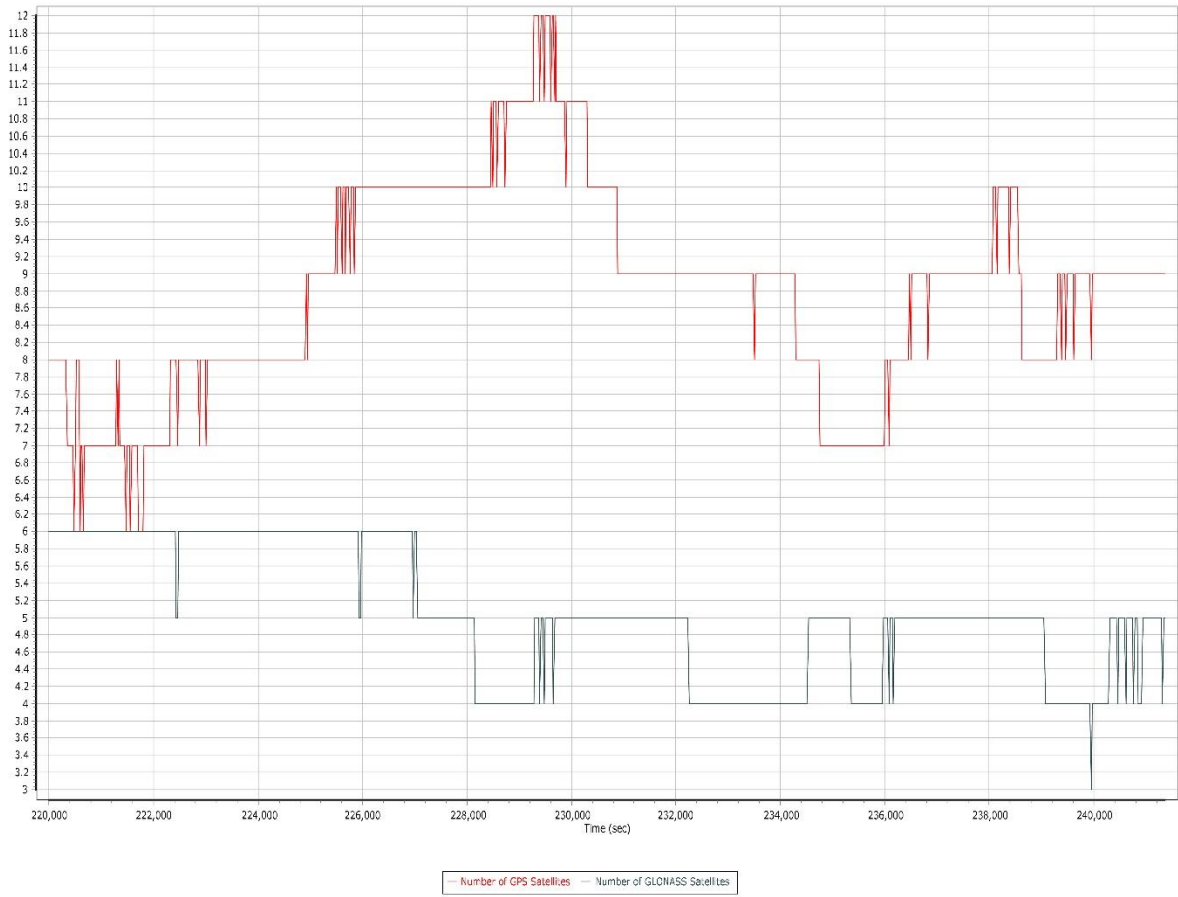


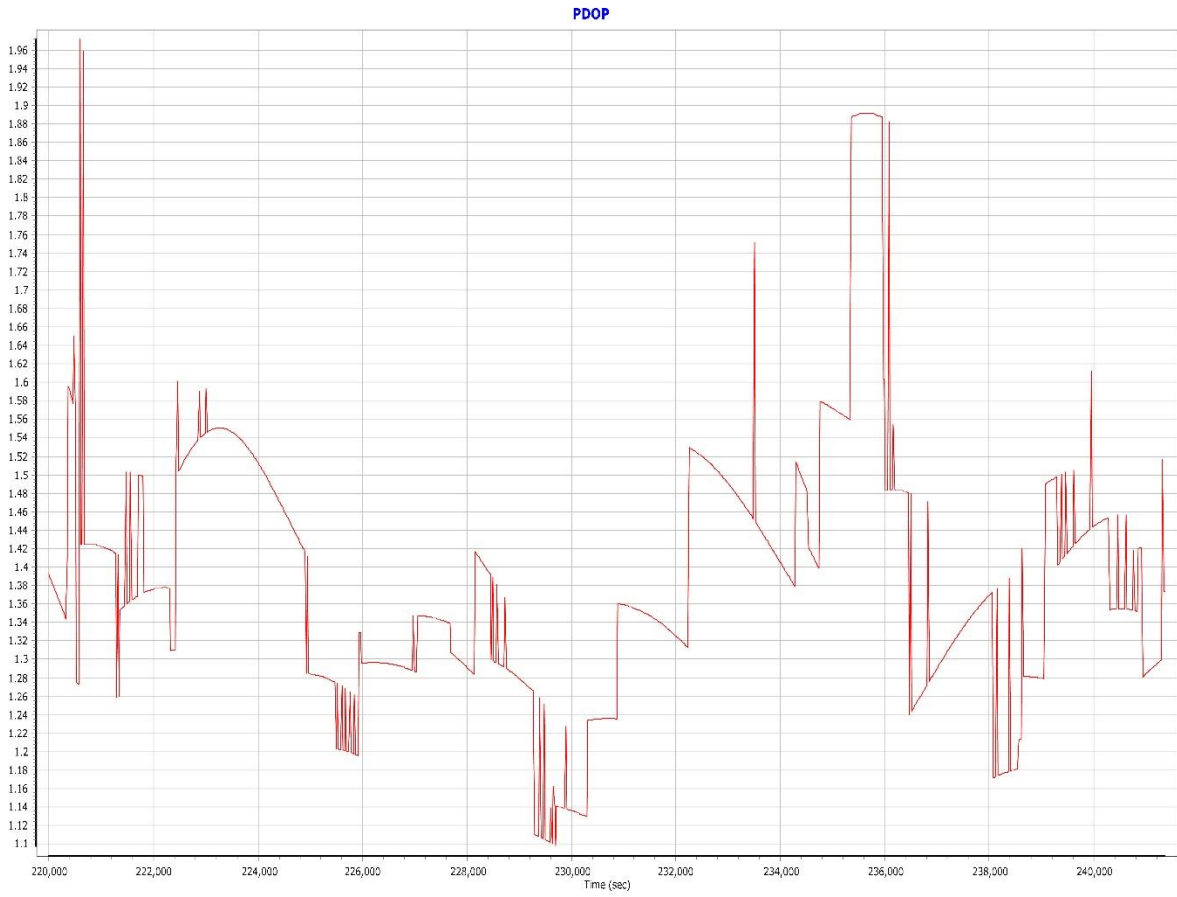
UNB18072A

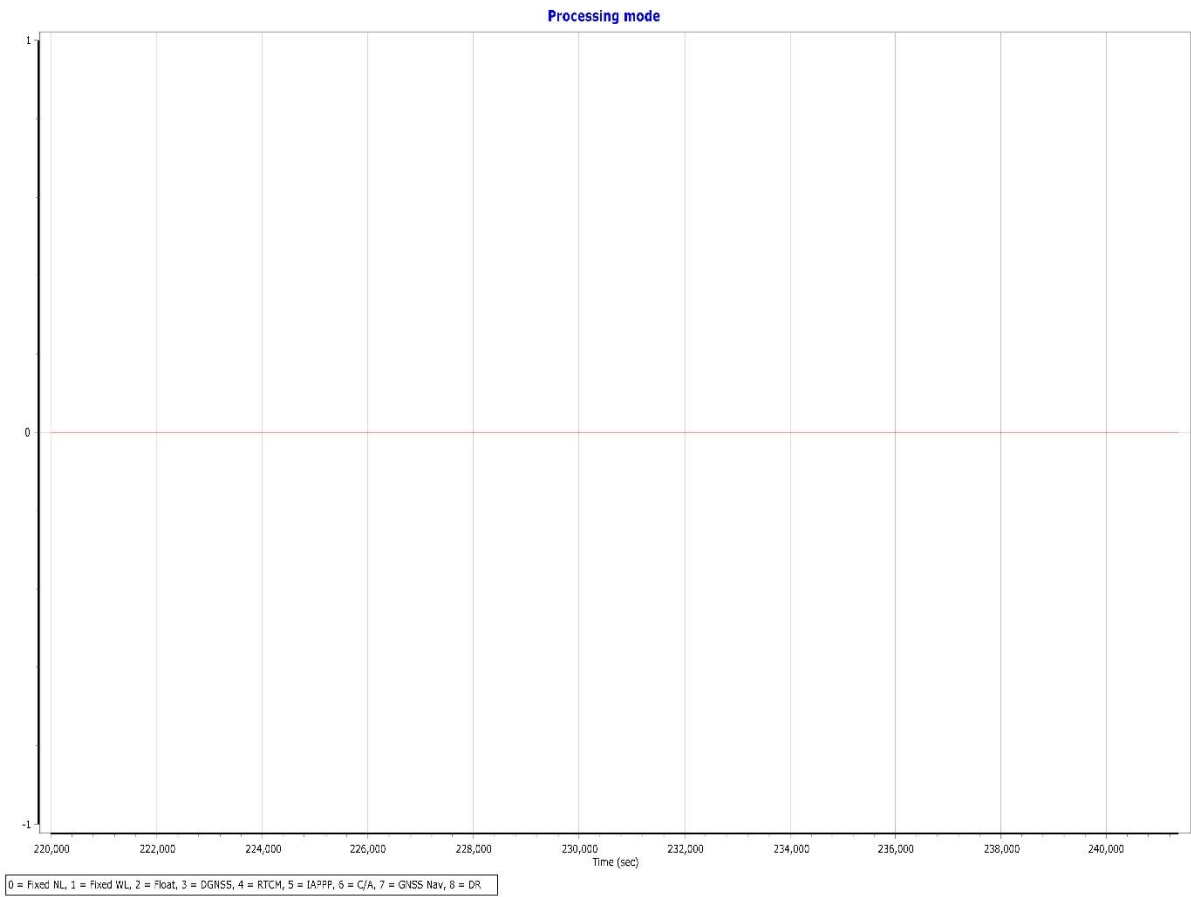


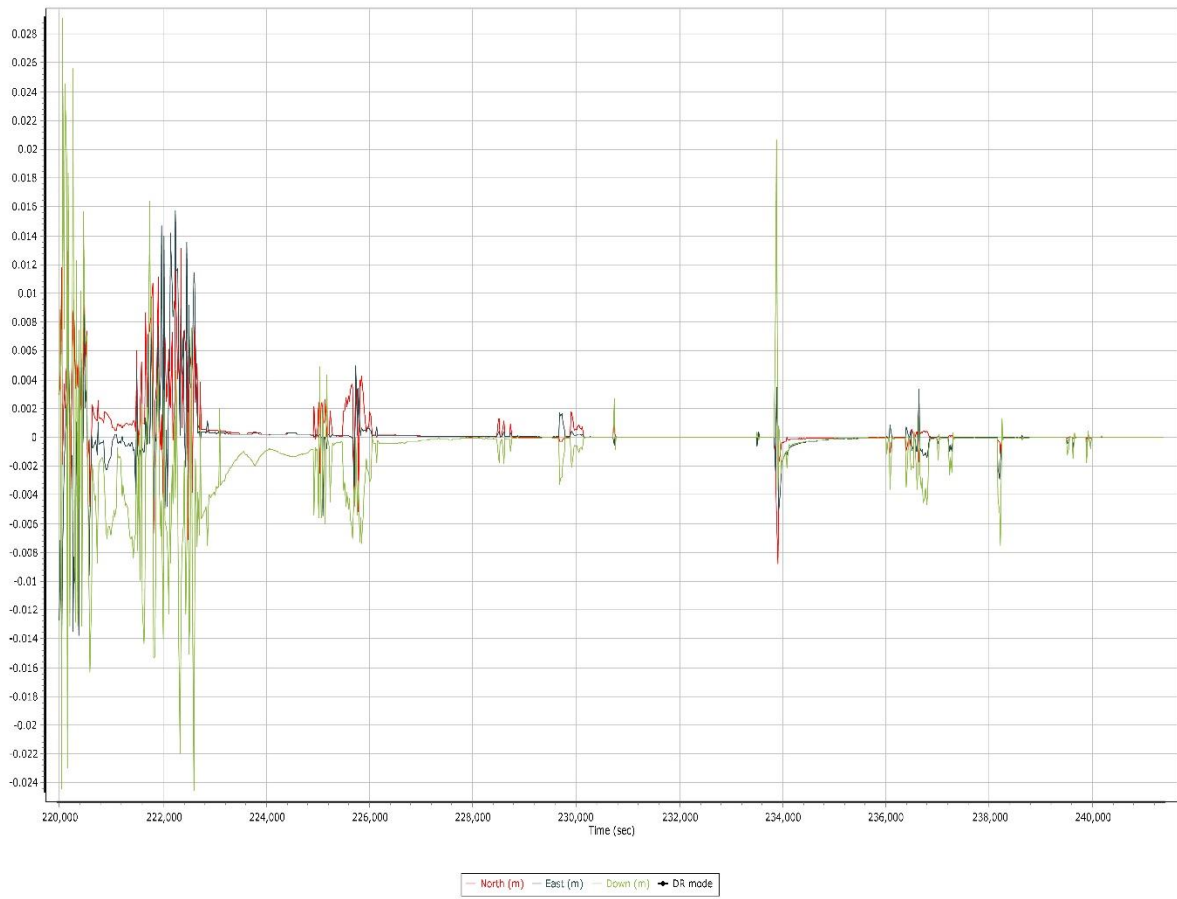


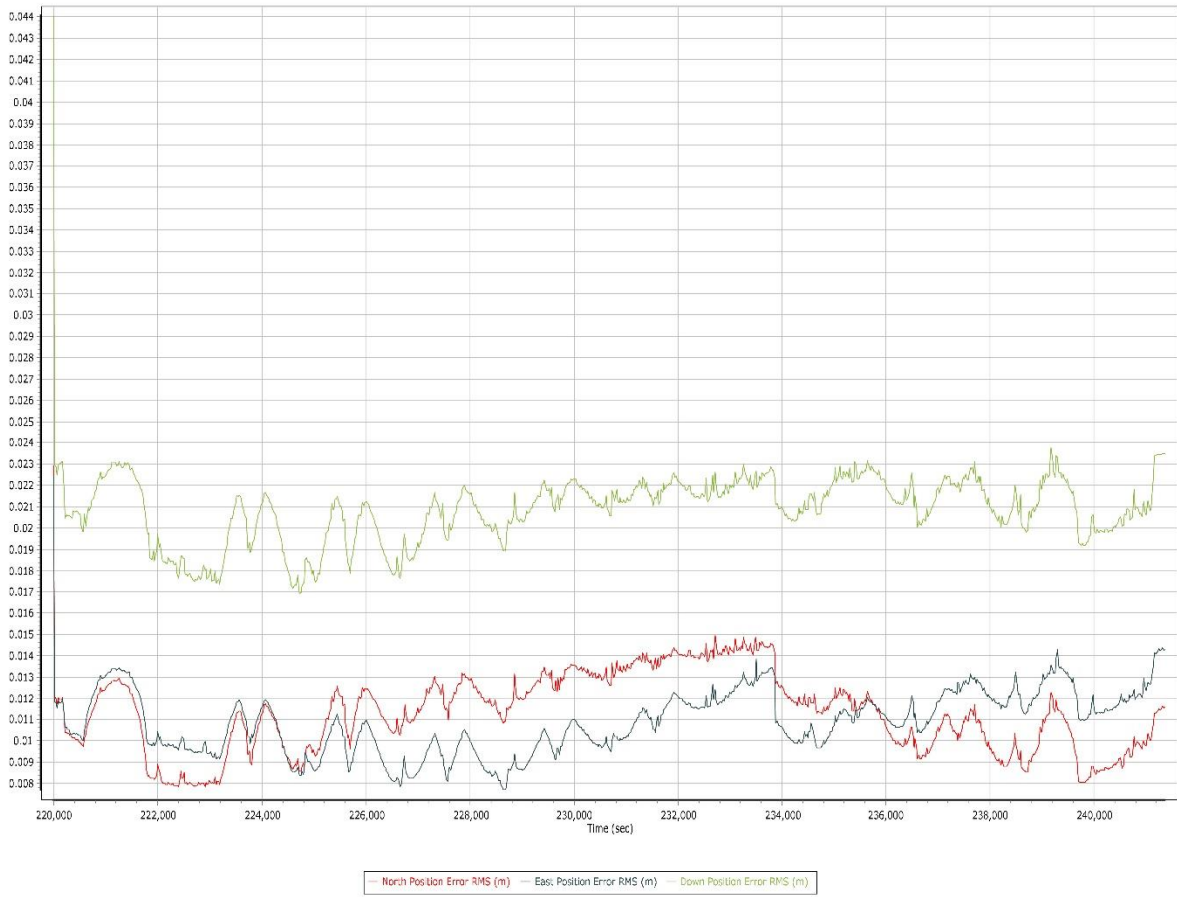


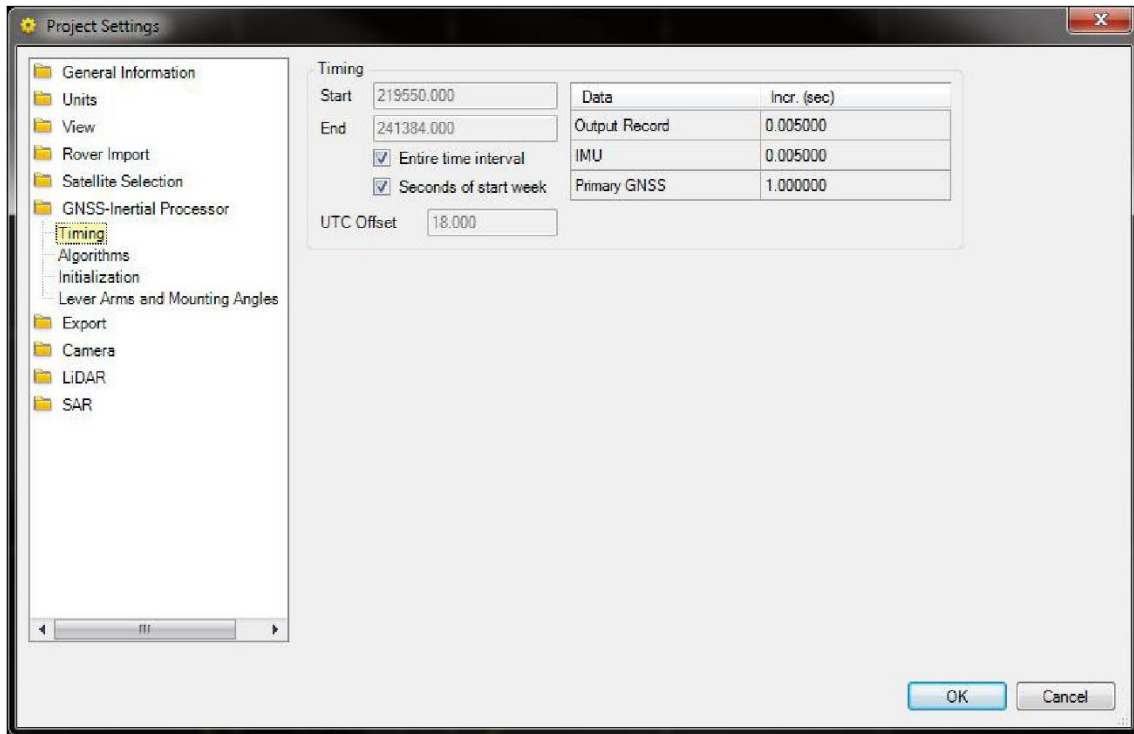


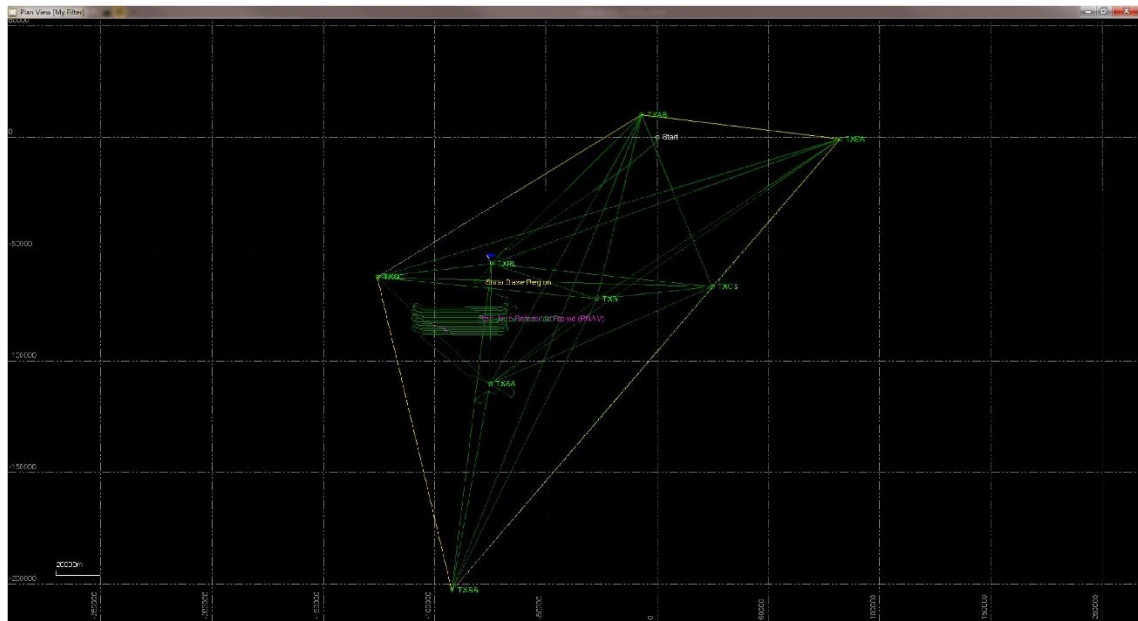


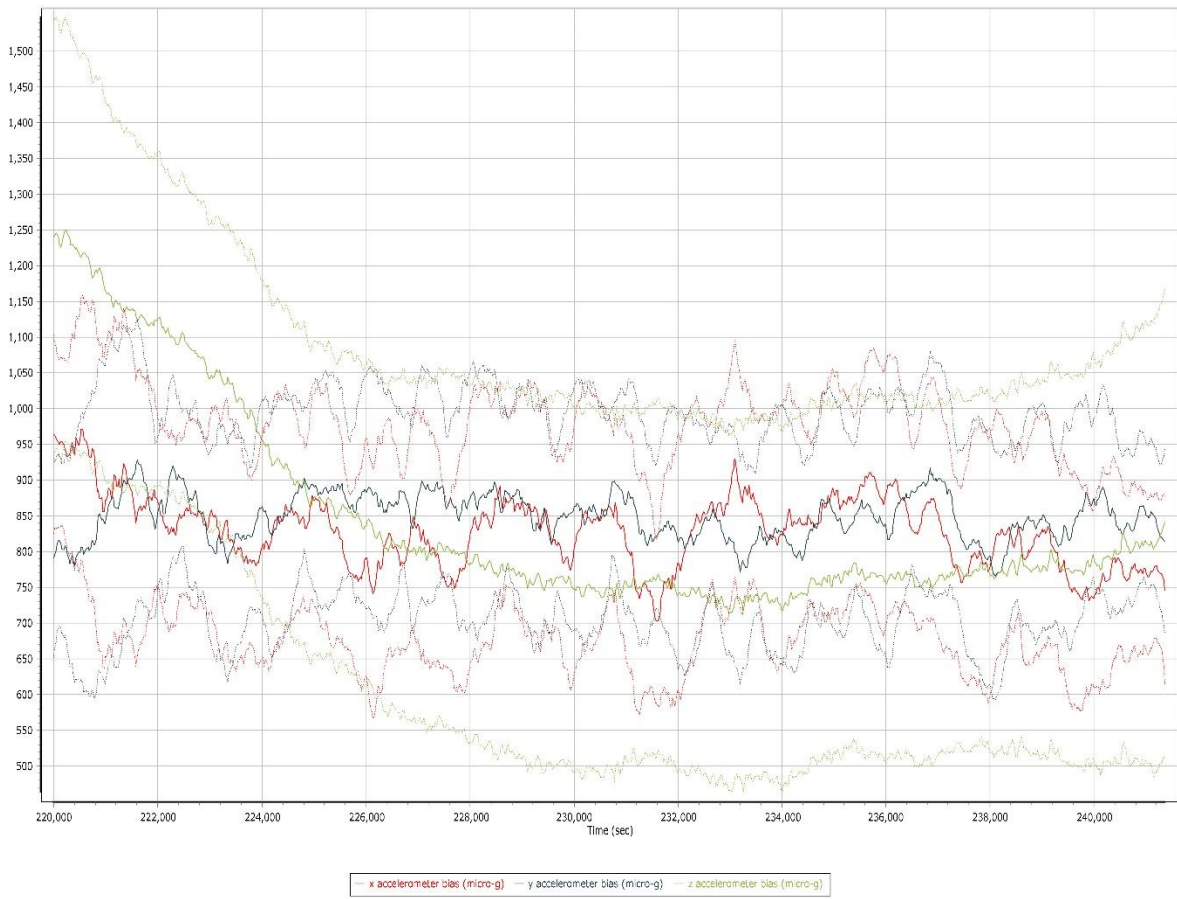


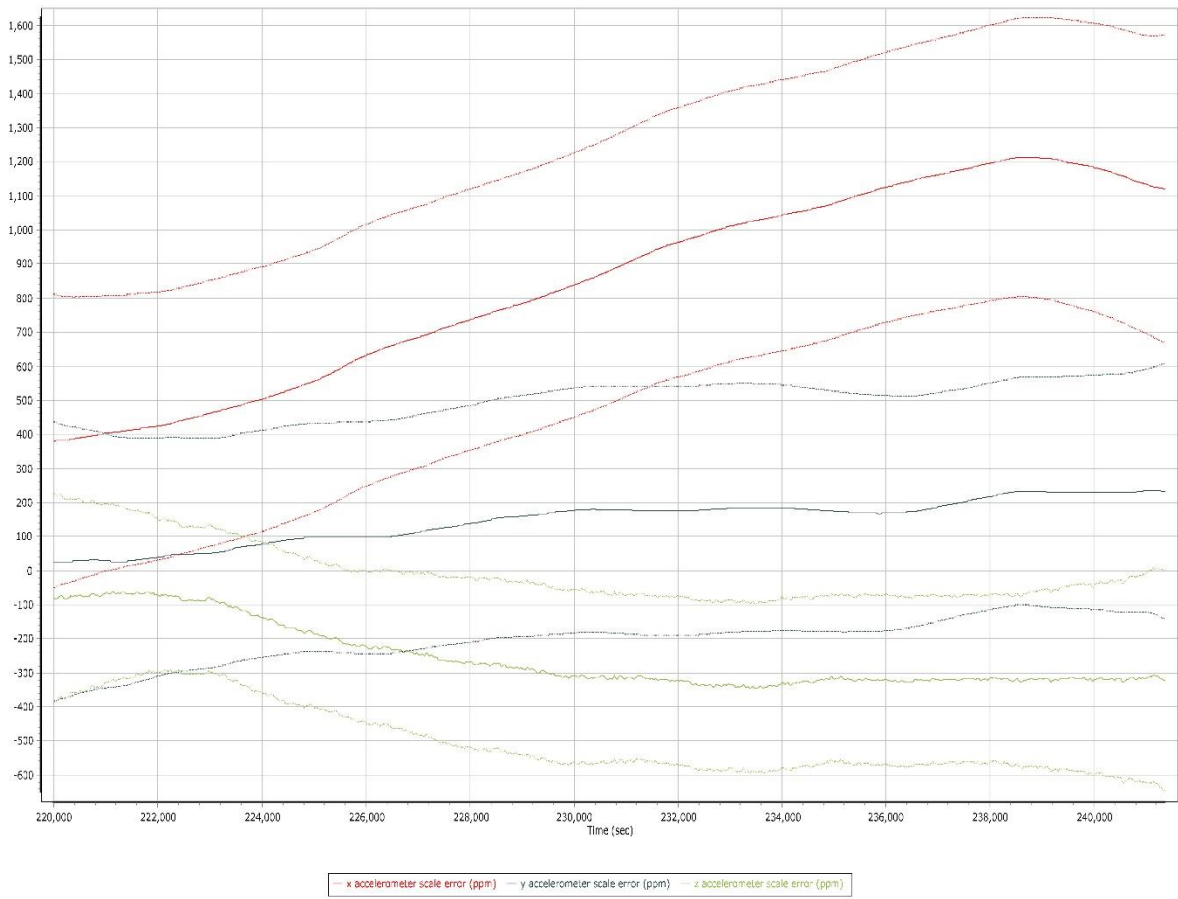


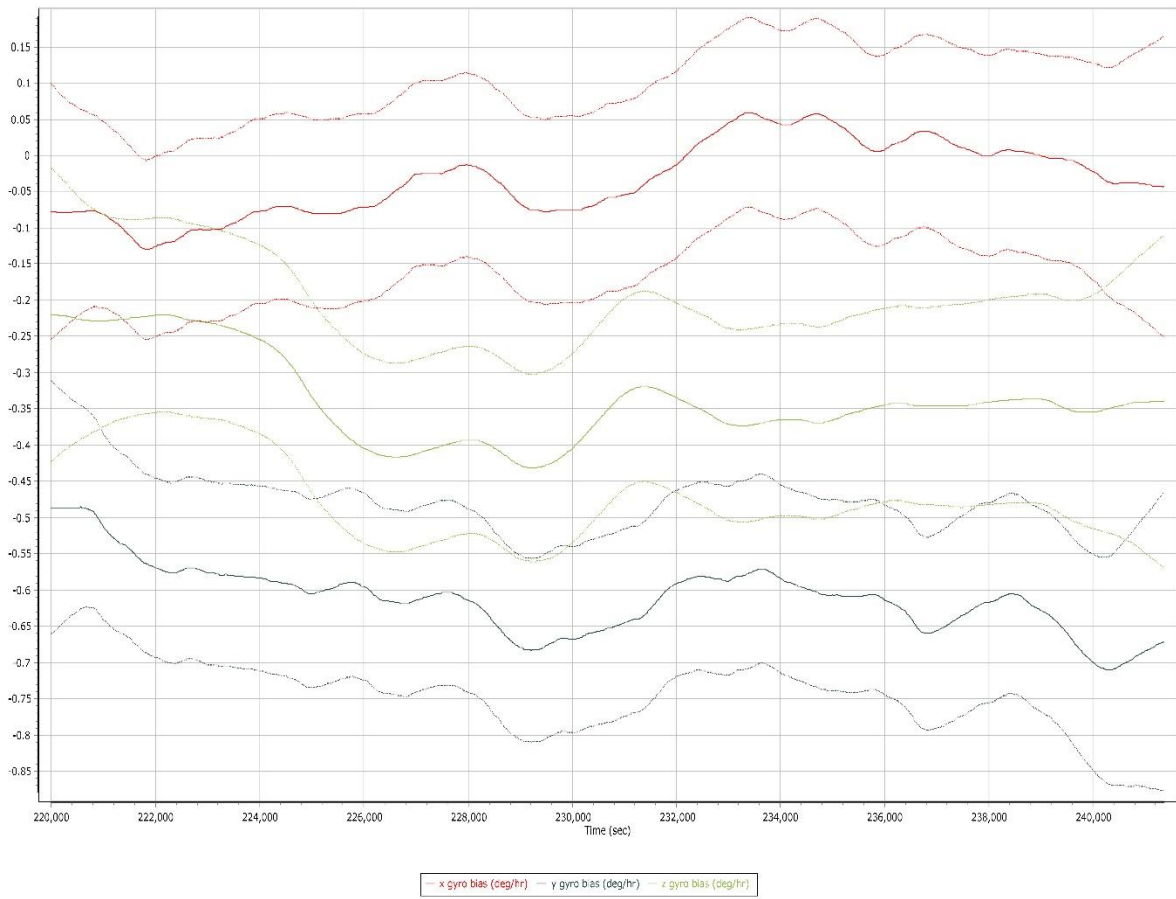


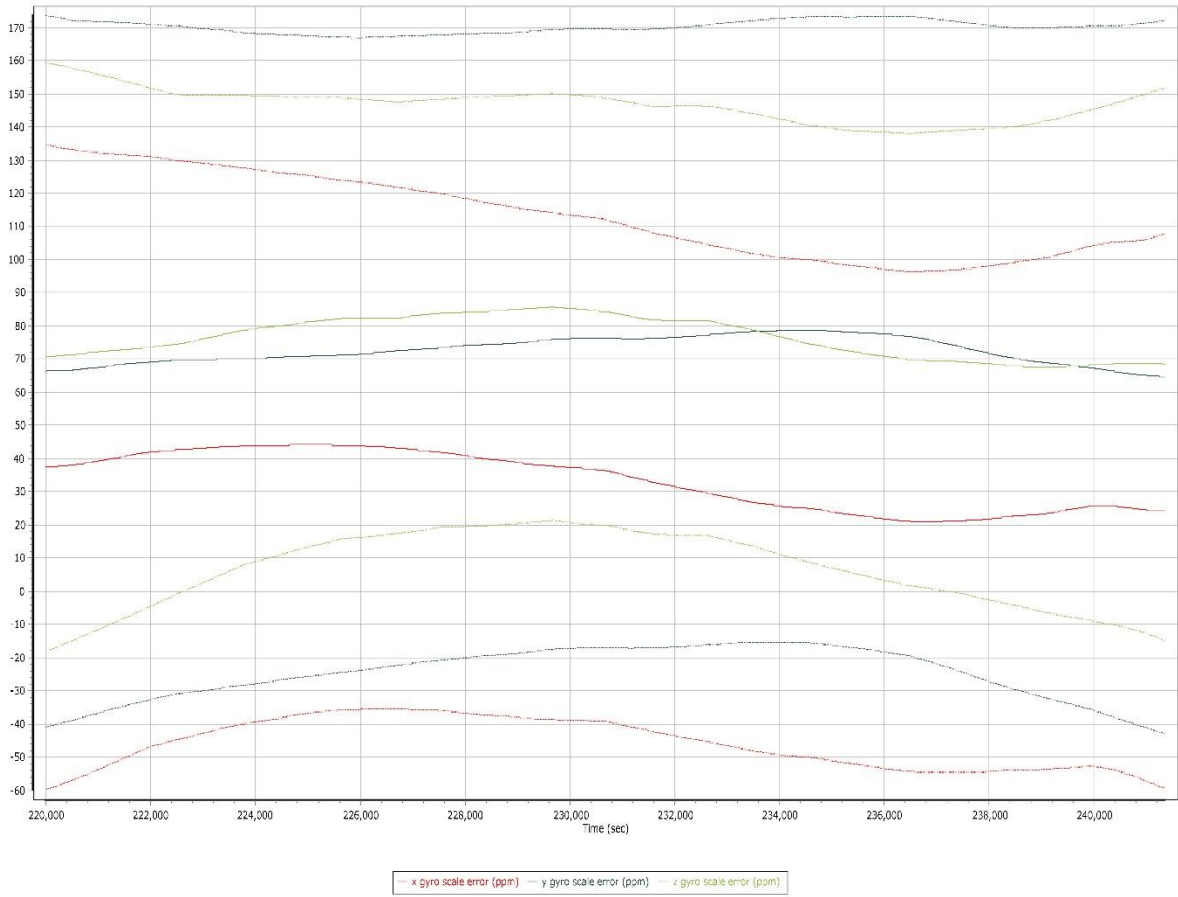




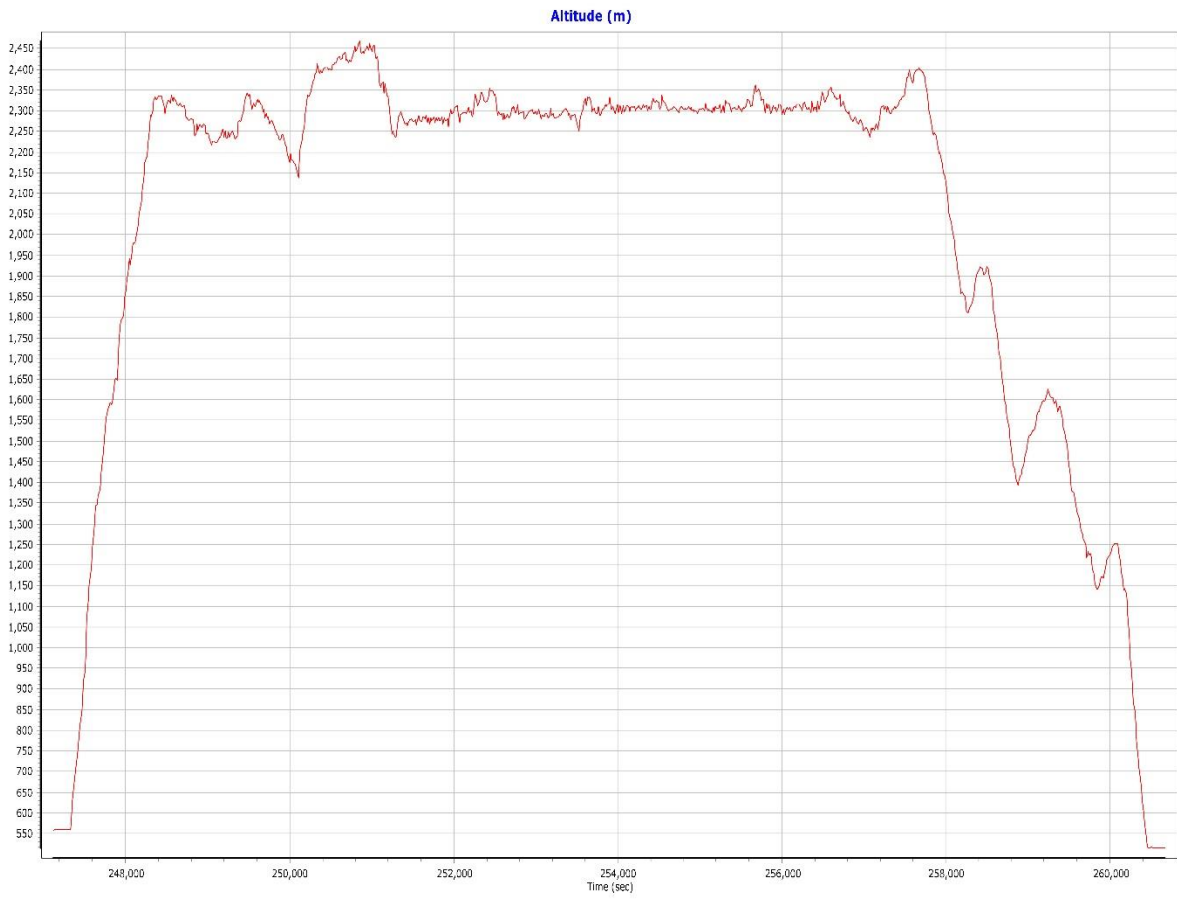


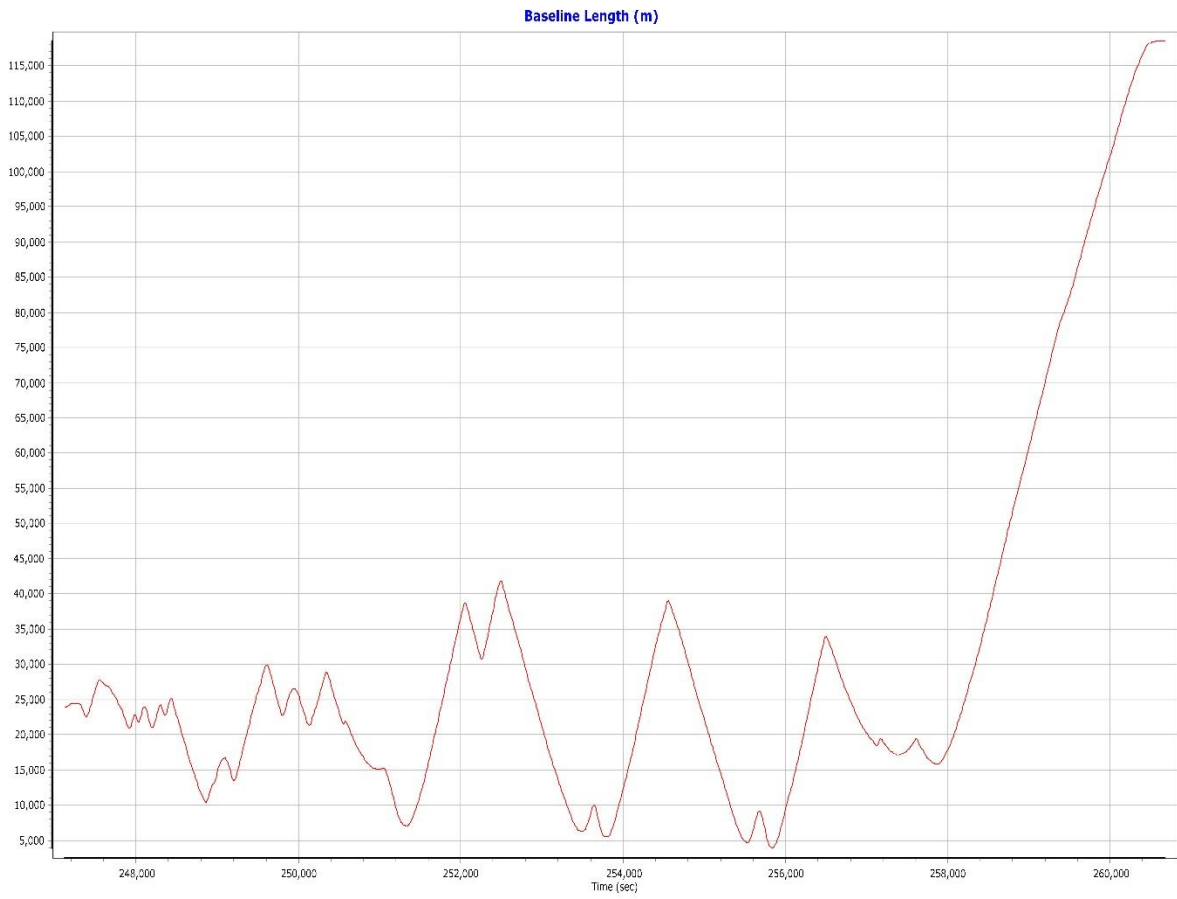


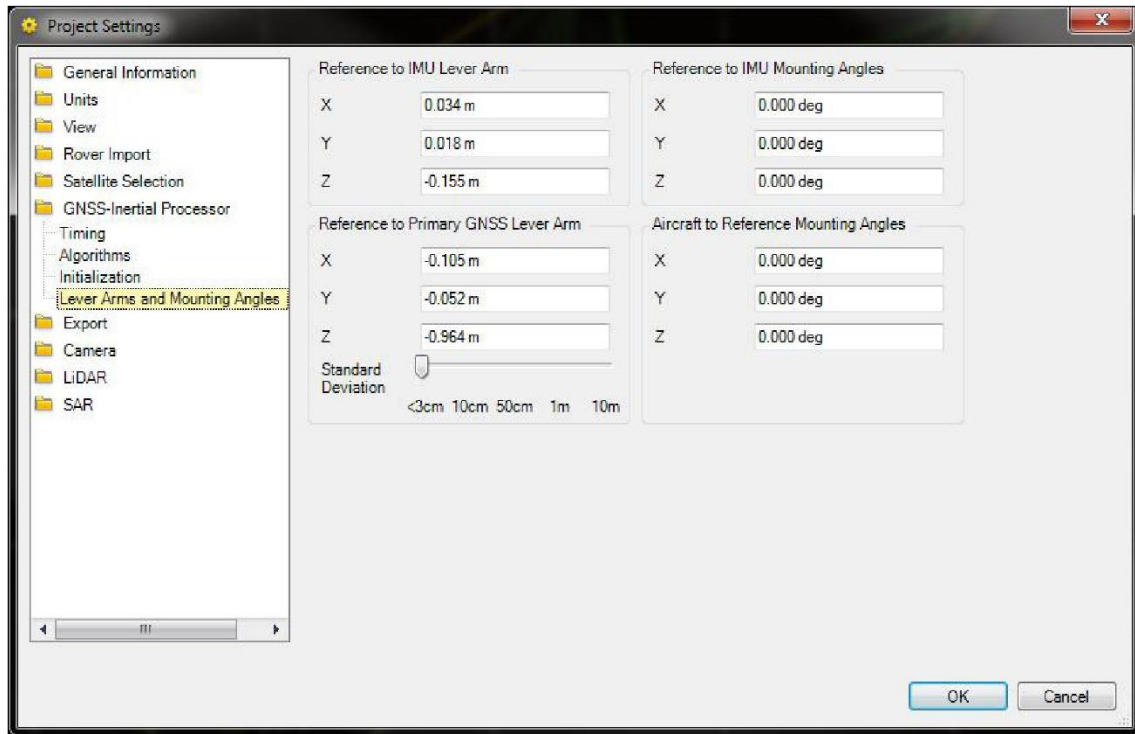


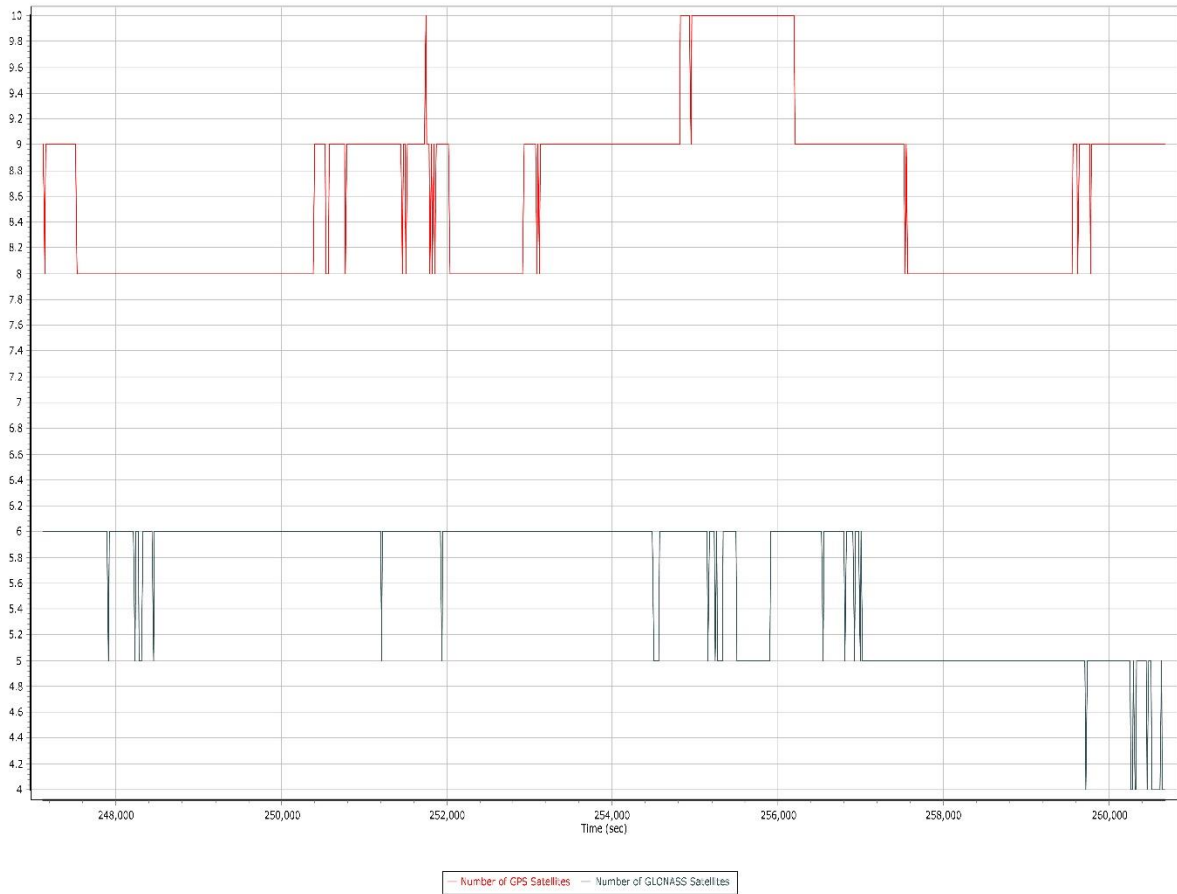


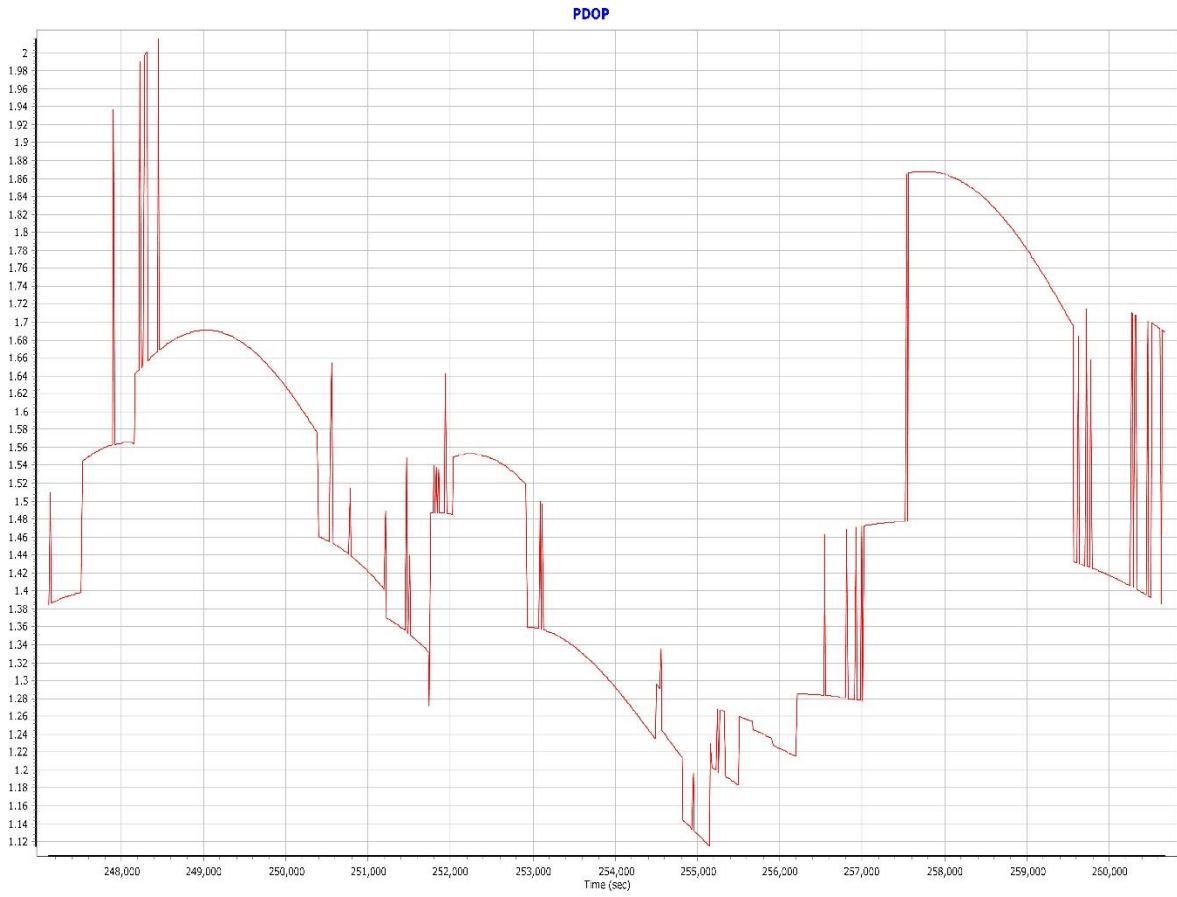
UNB18072B

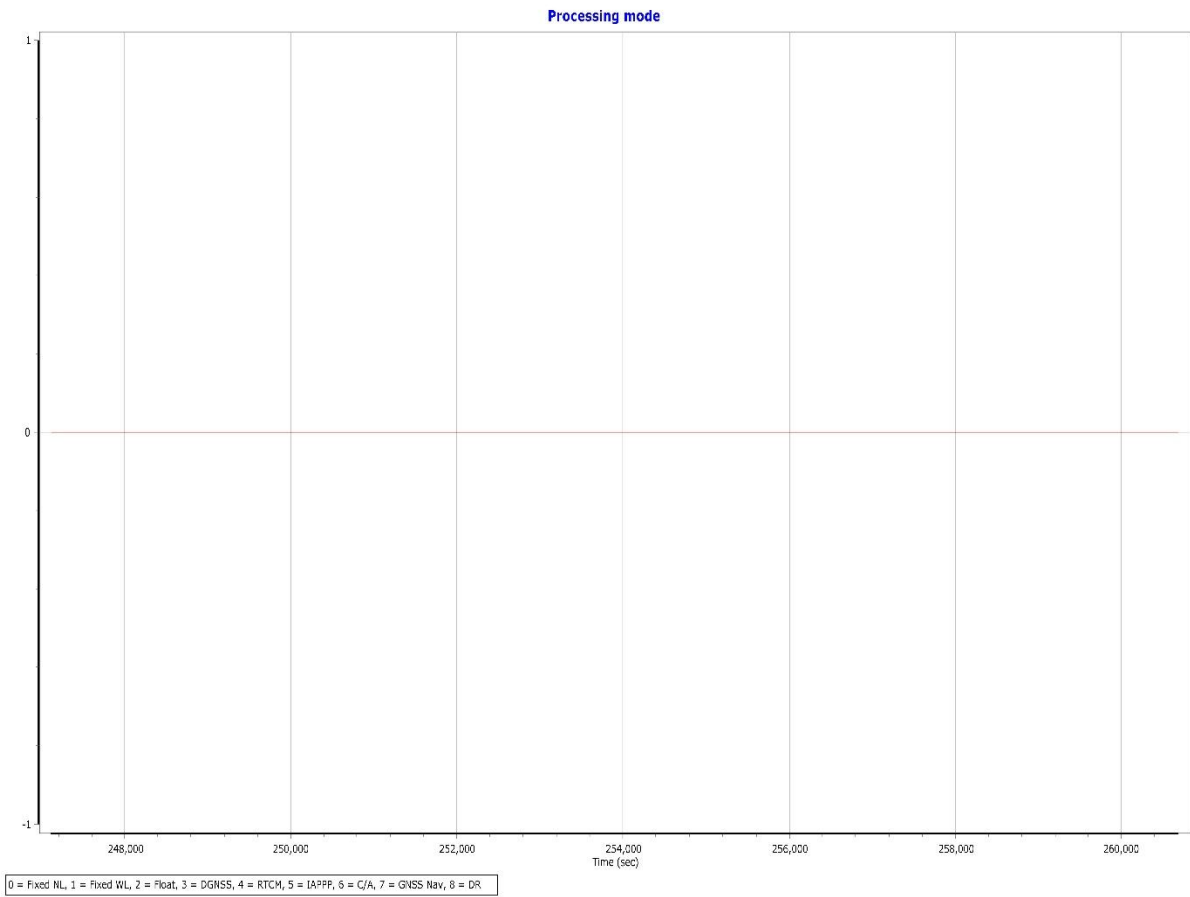


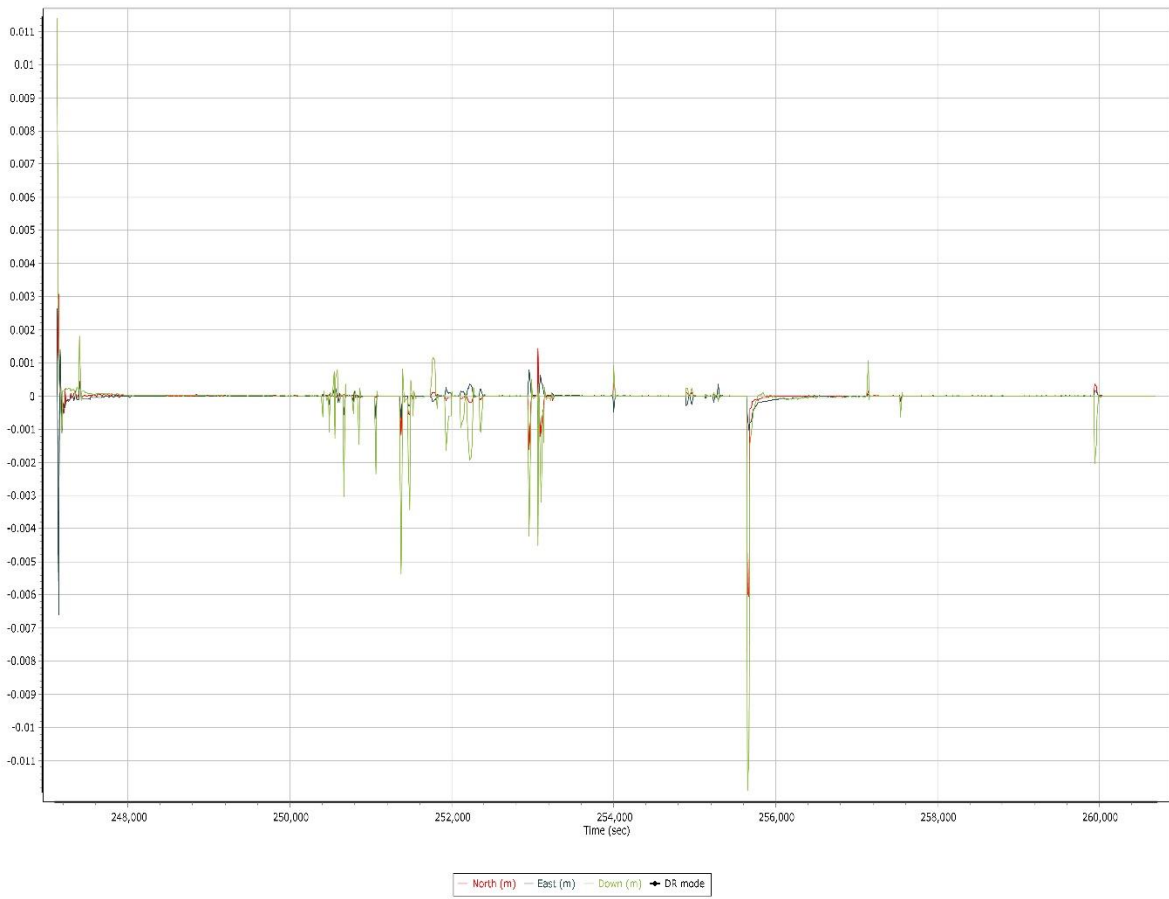


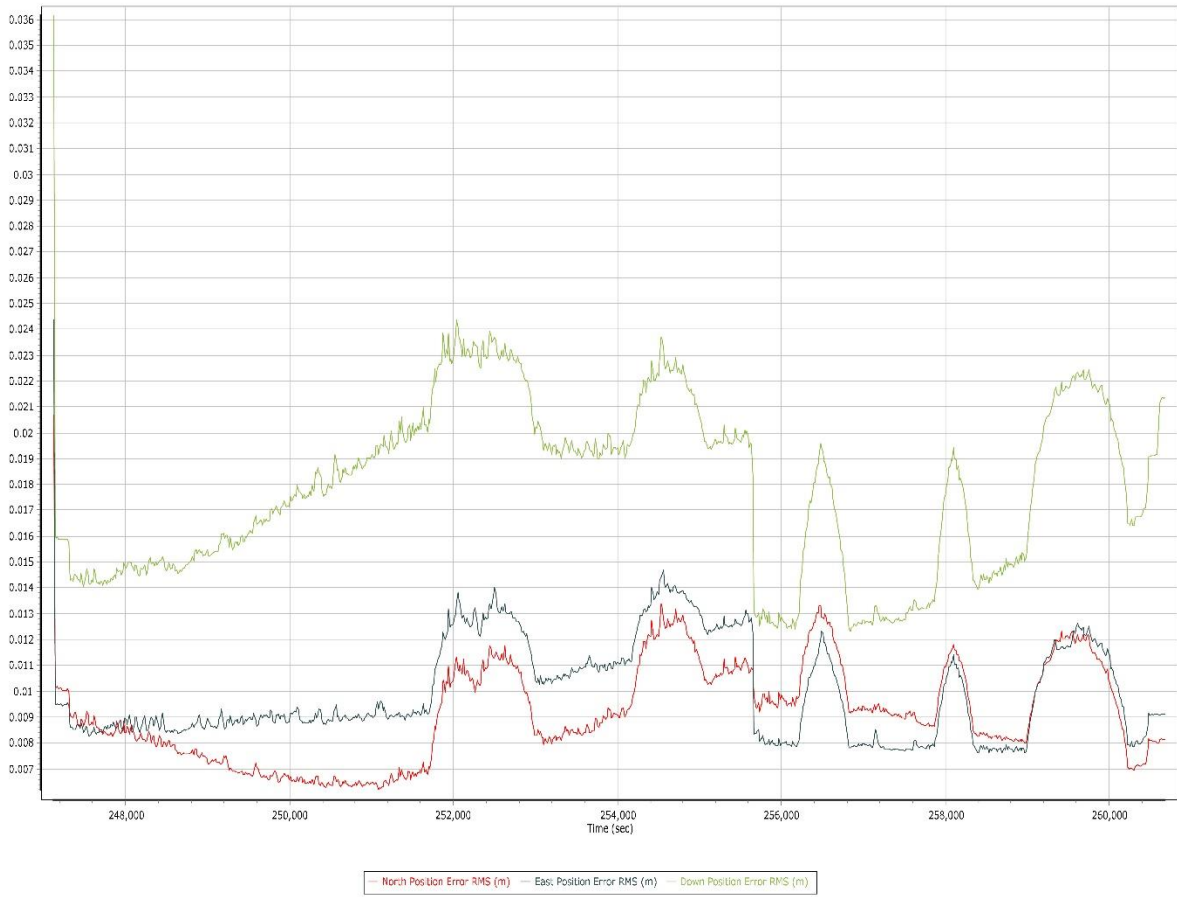


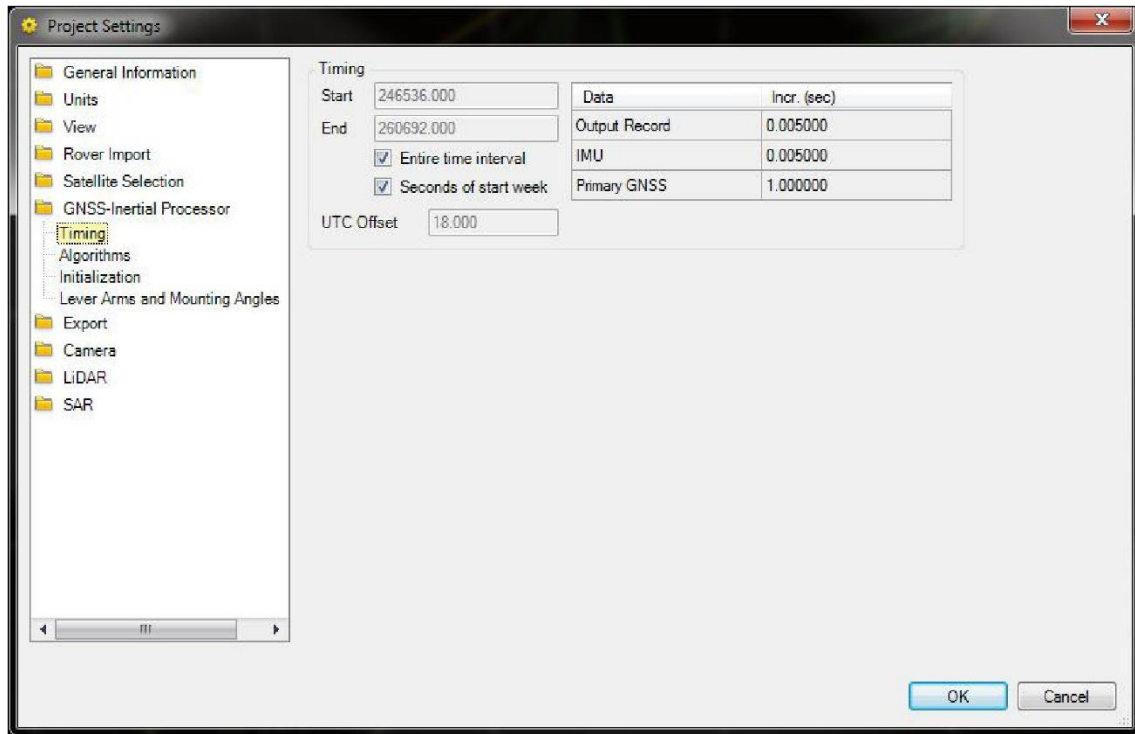


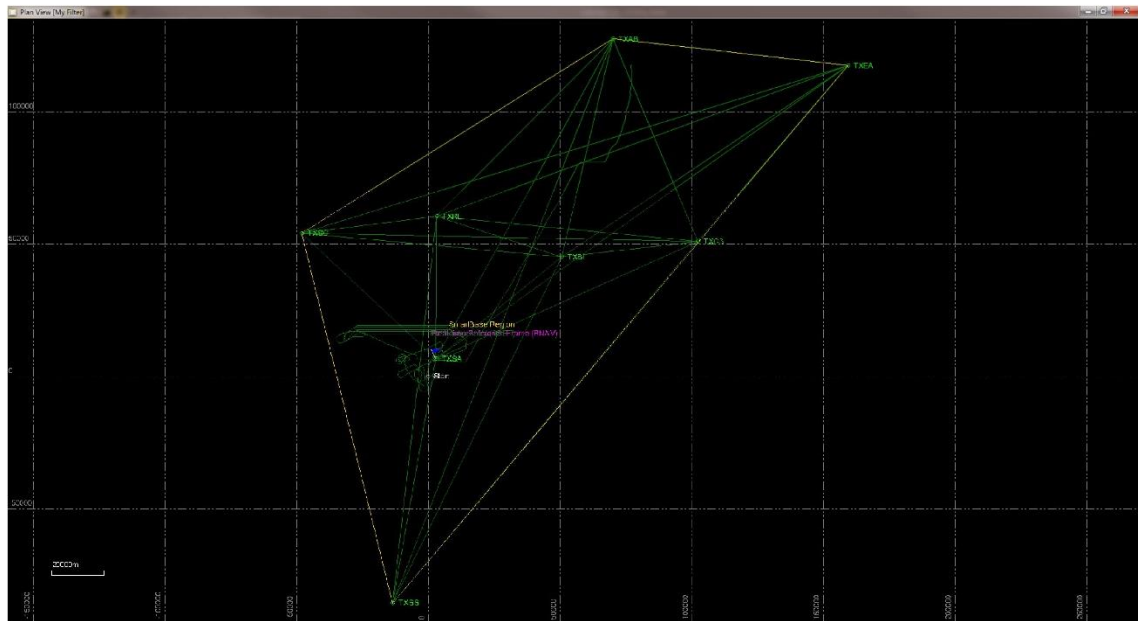


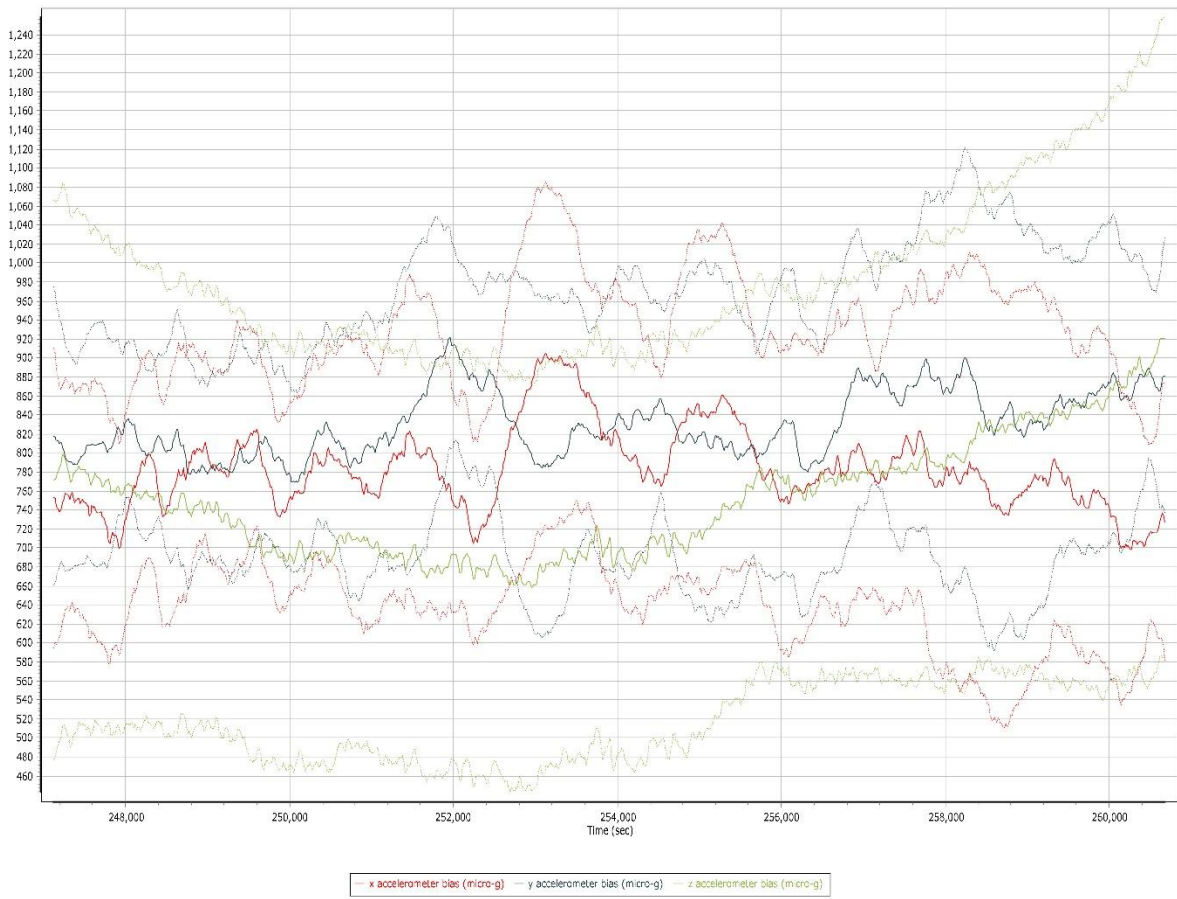


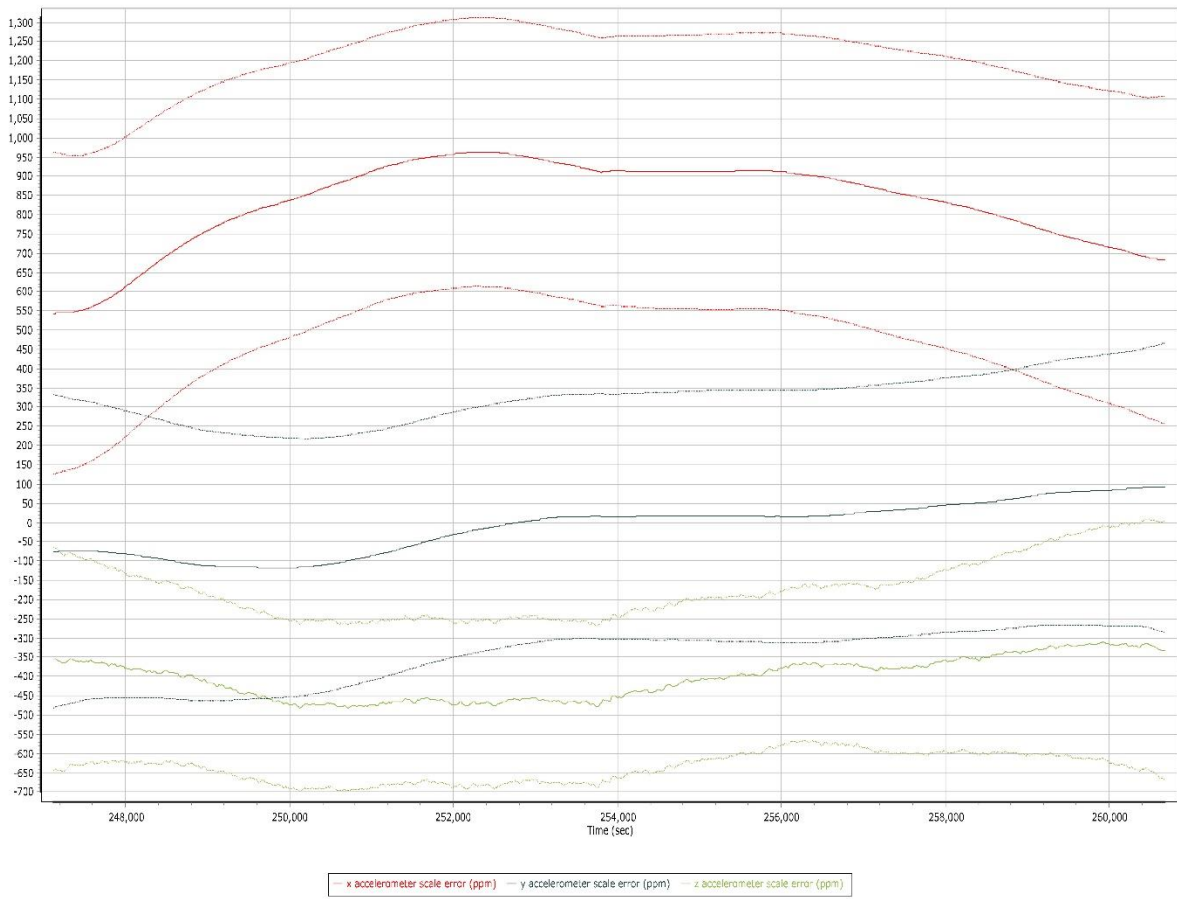


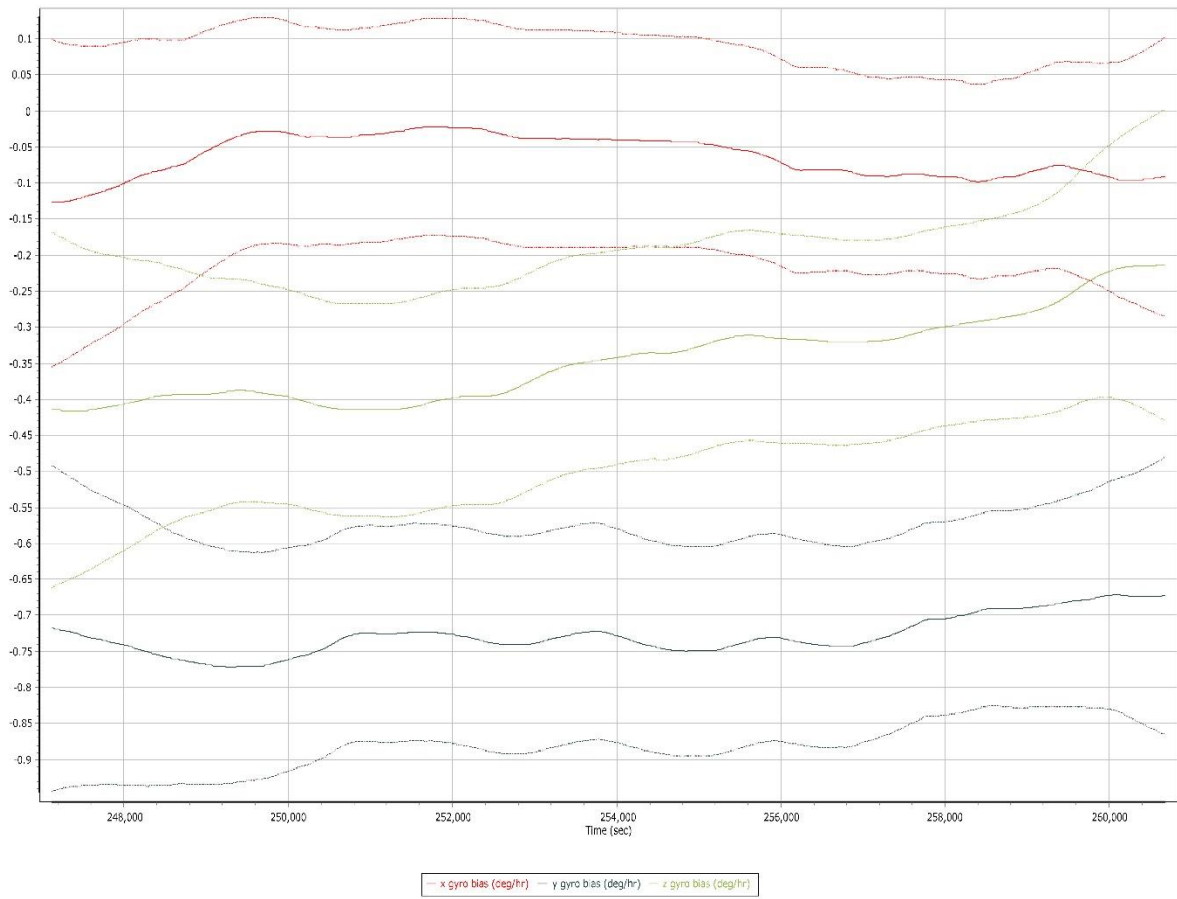


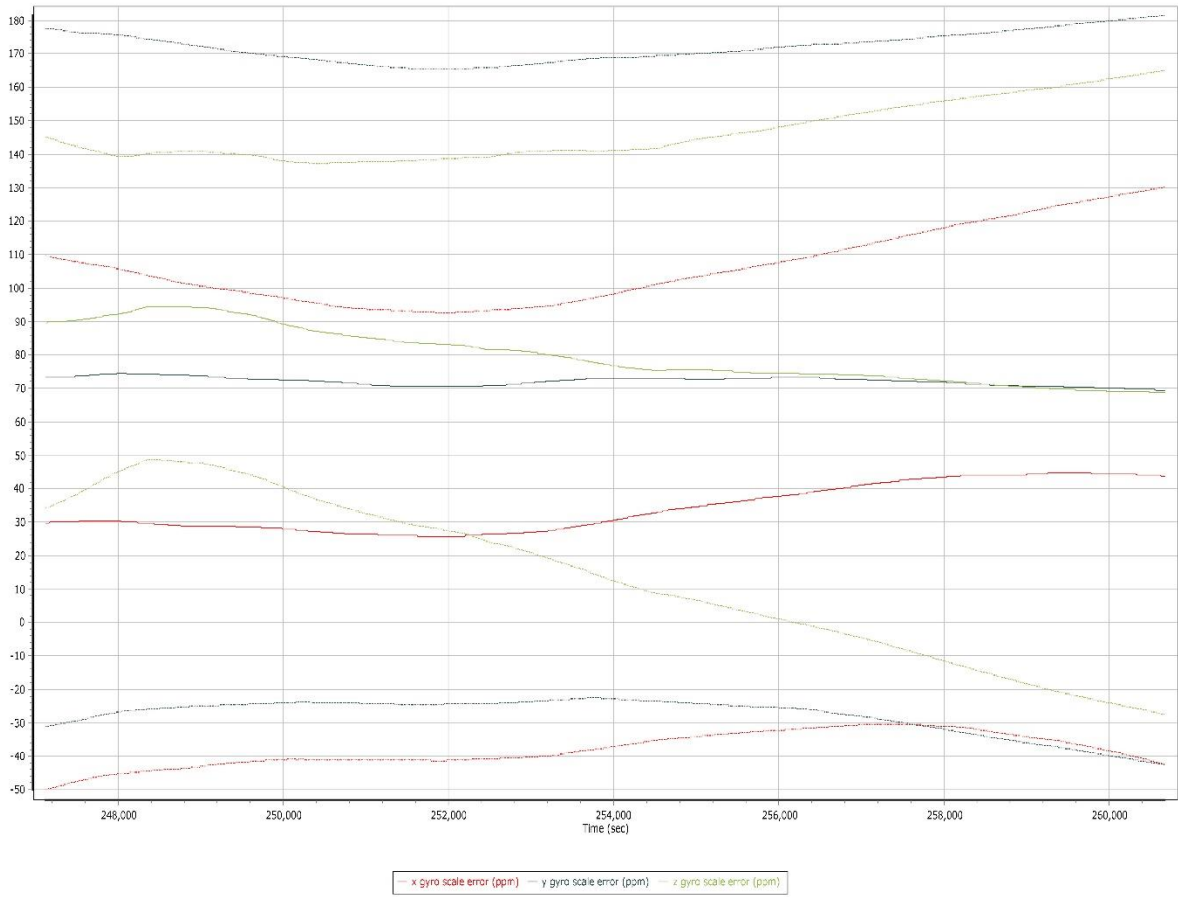




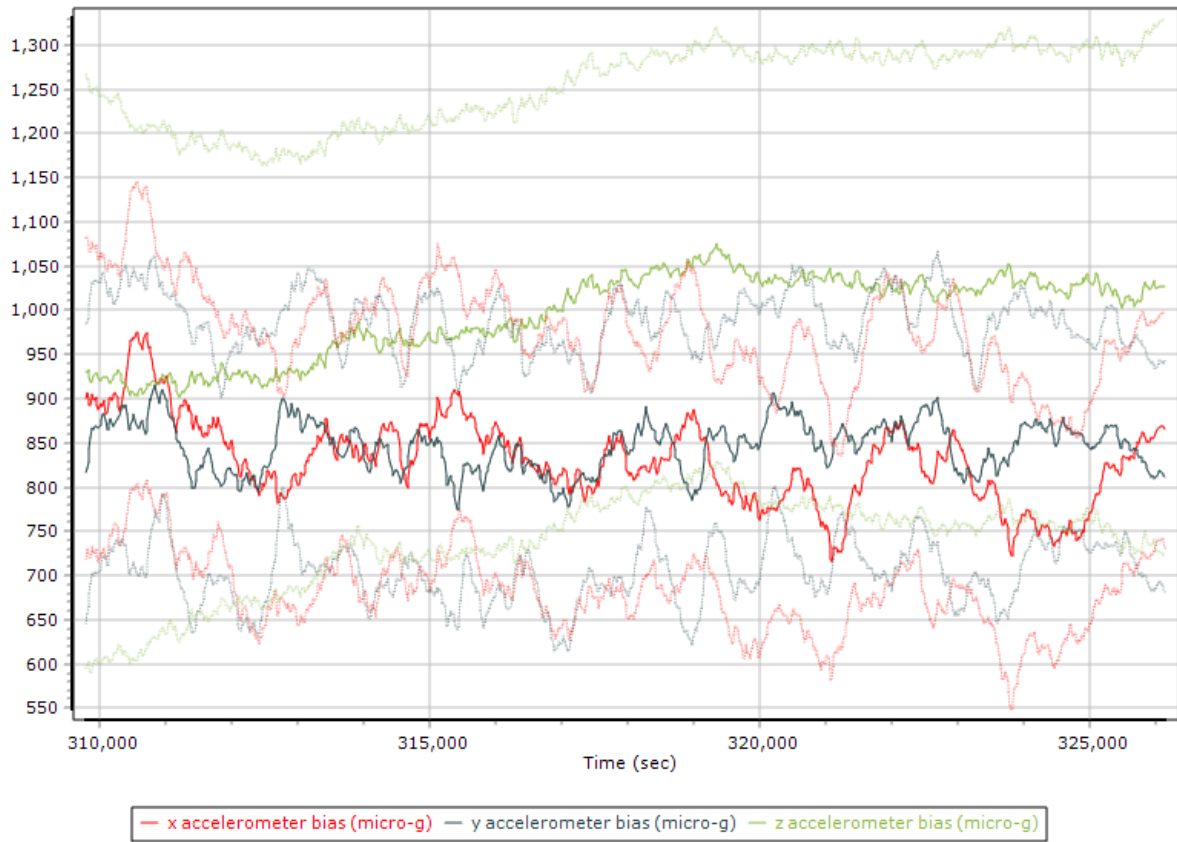


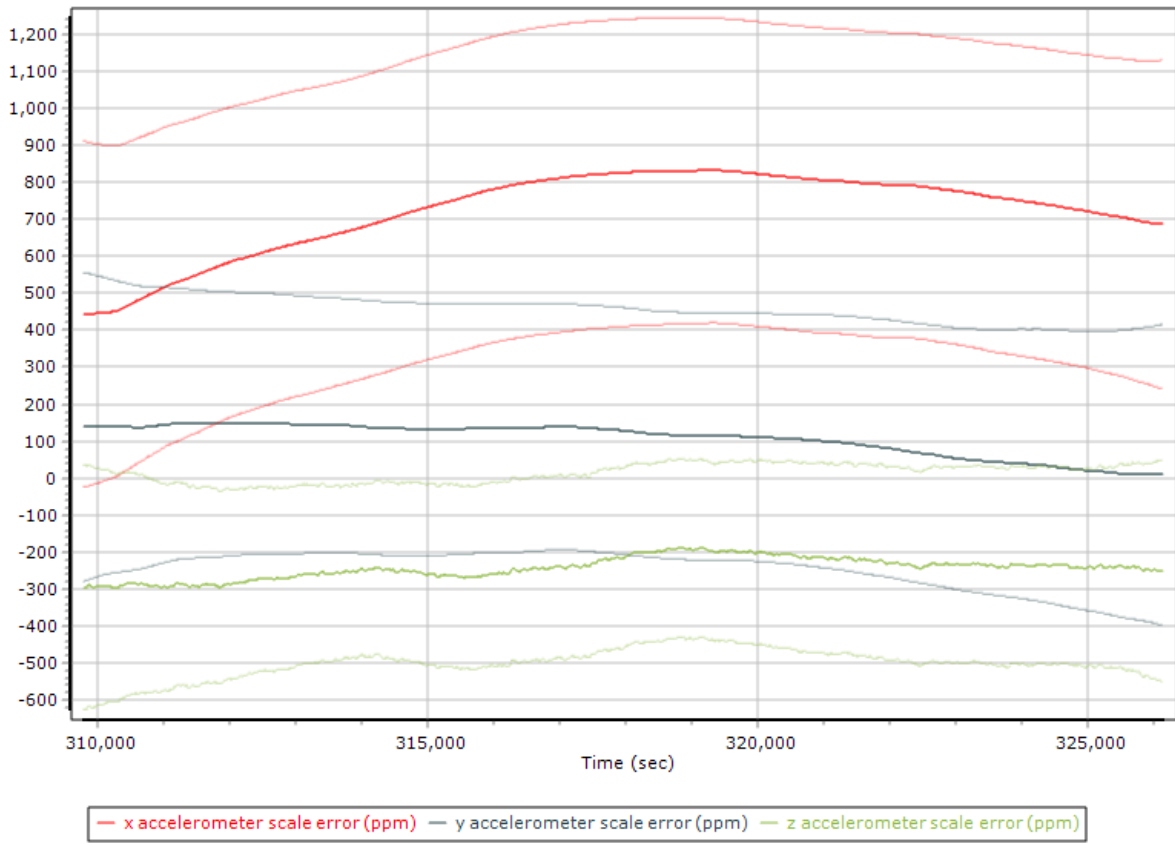


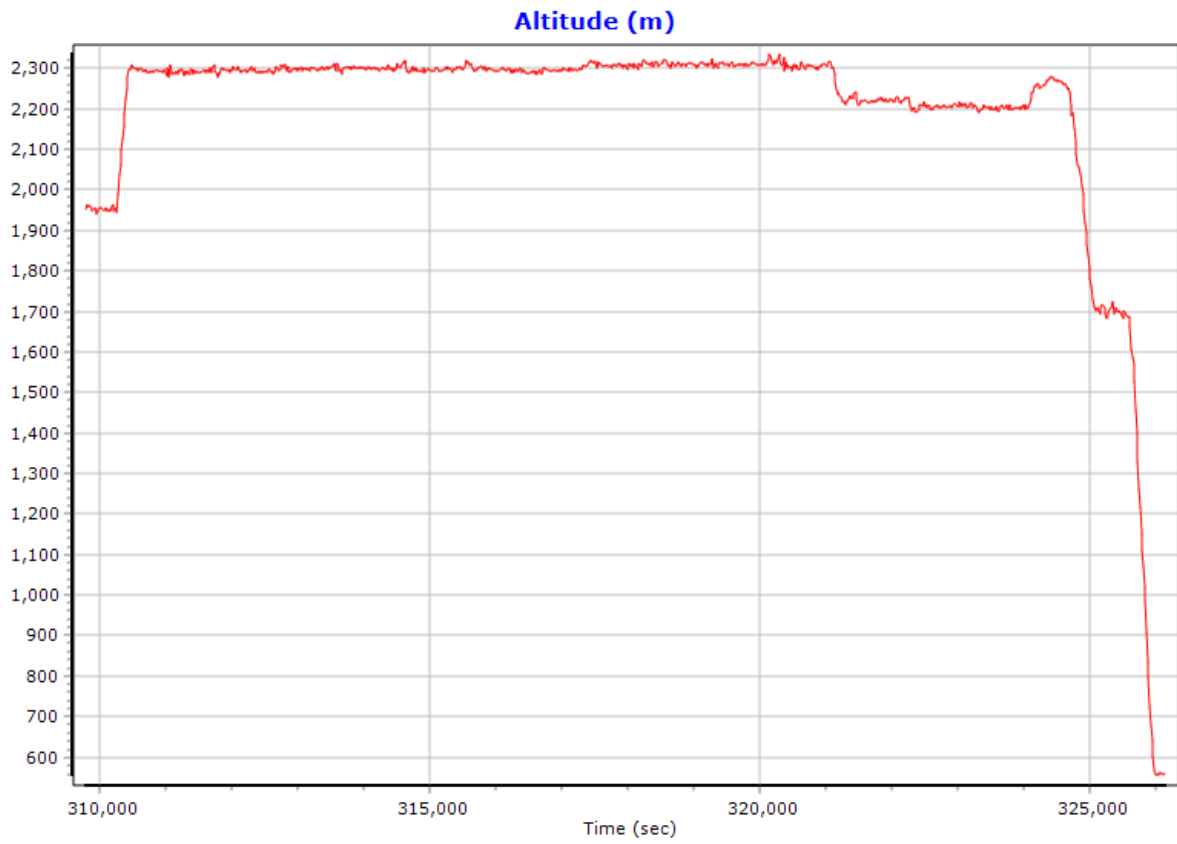


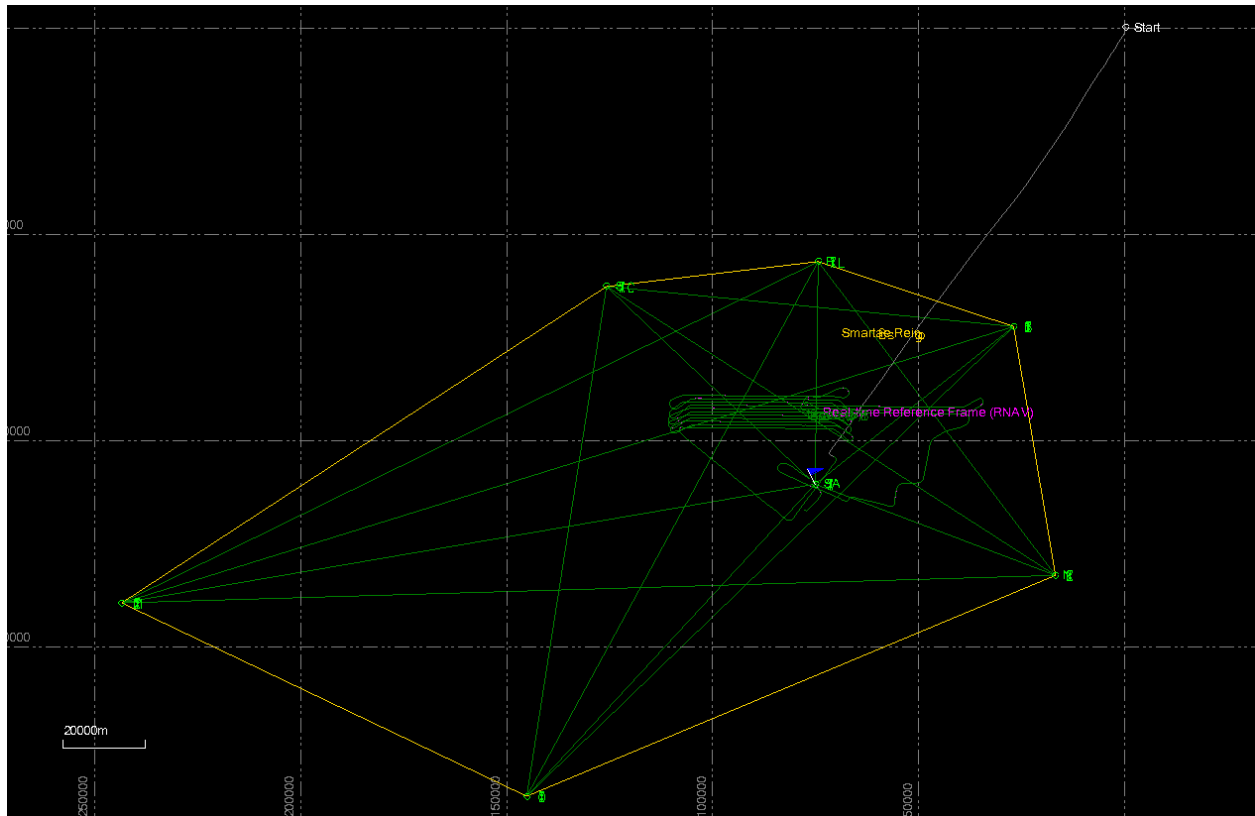
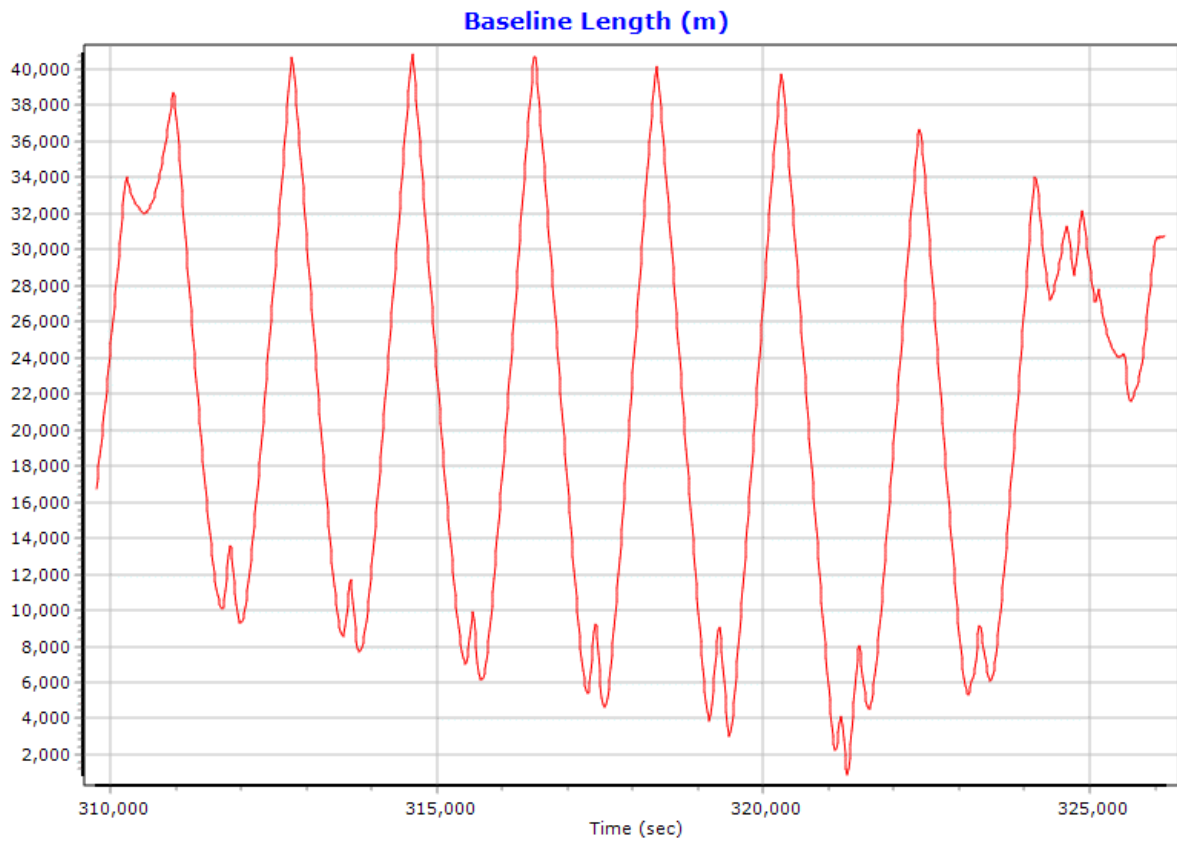


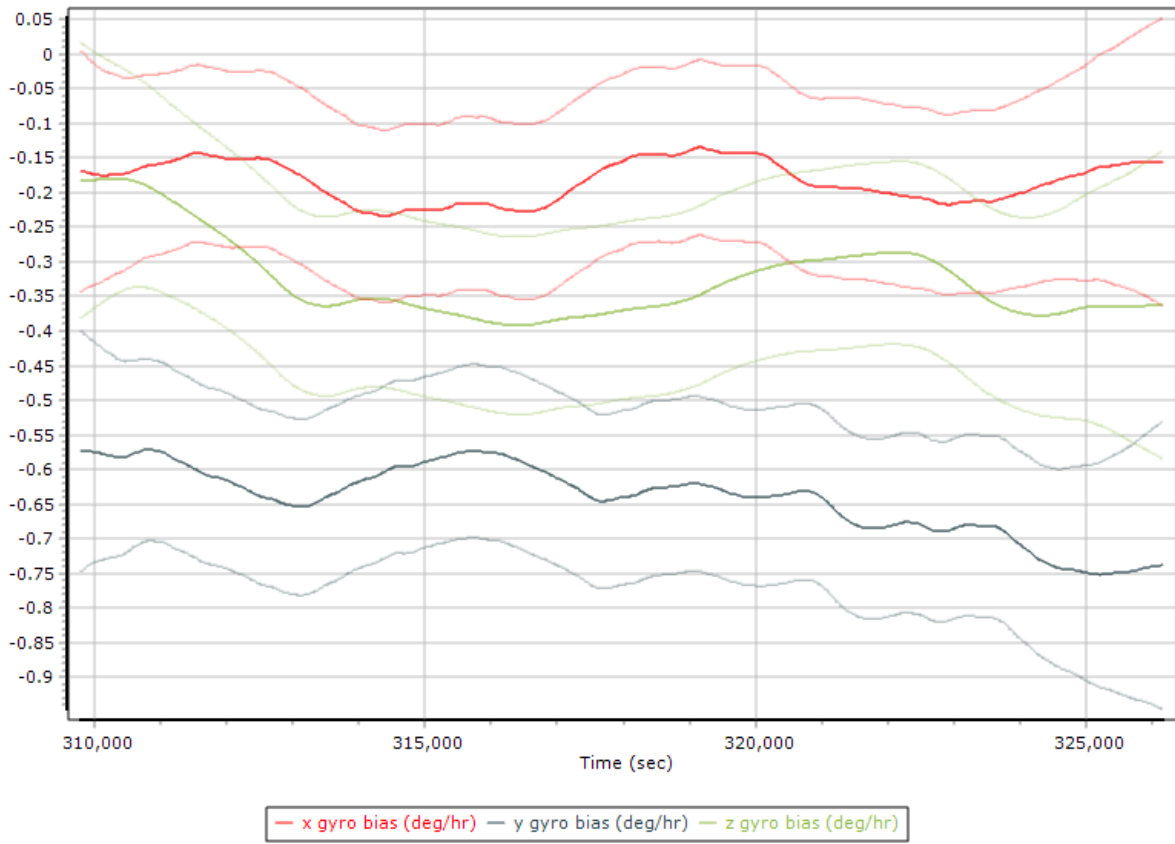
UNB18073A

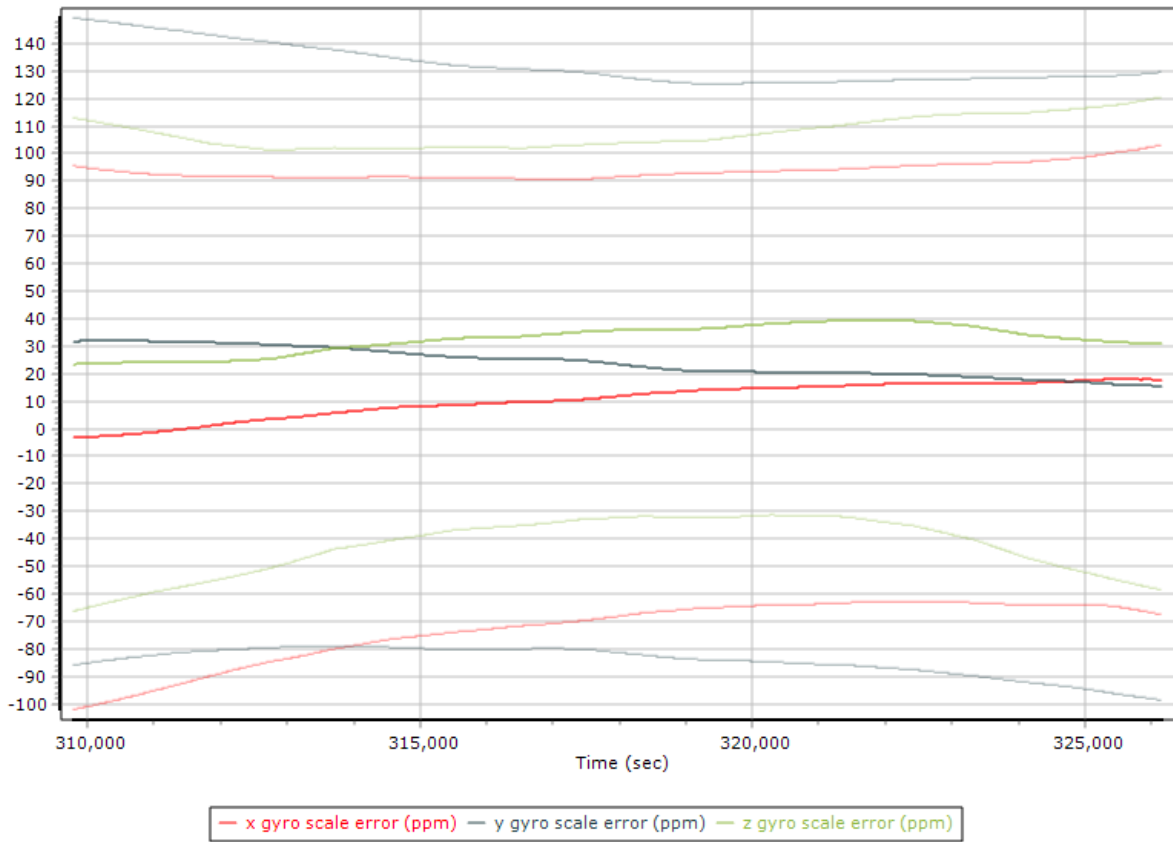












Project Settings [X]

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation: (Selected)

<3cm 10cm 50cm 1m 10m

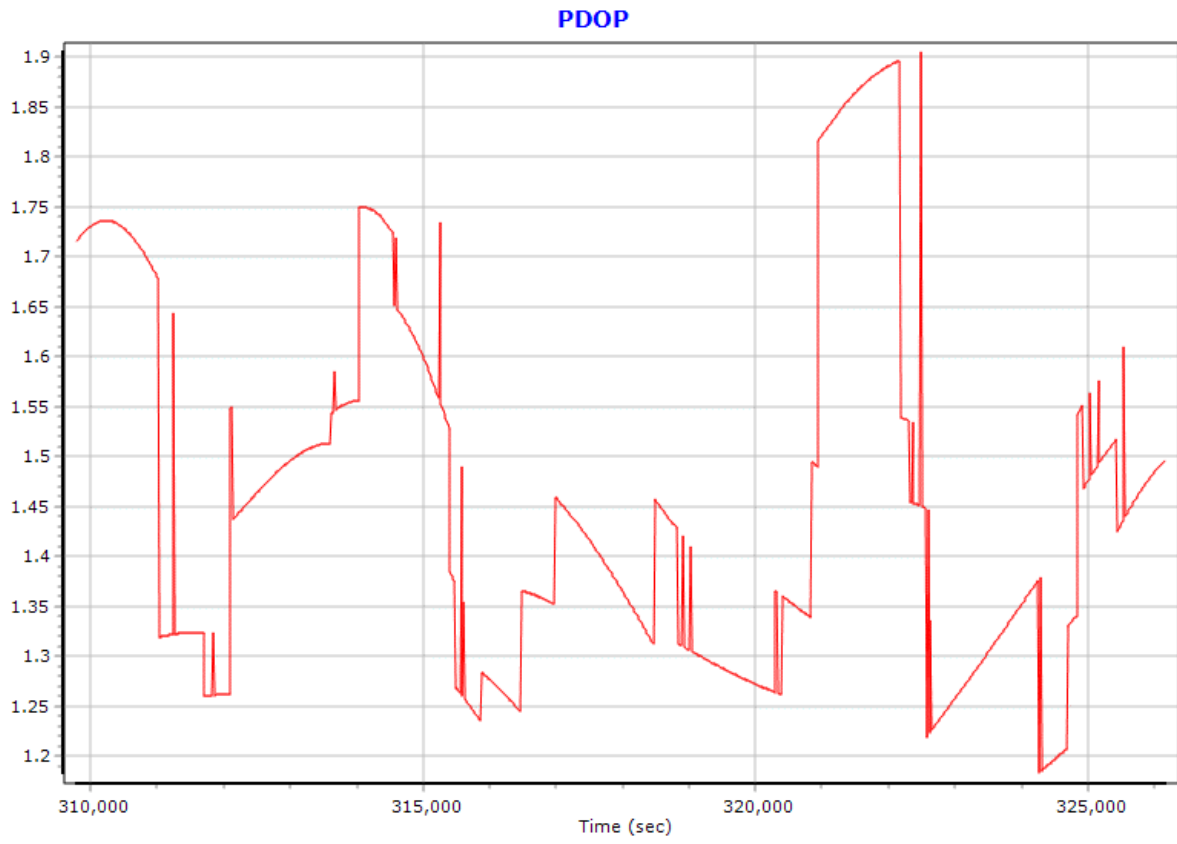
Aircraft to Reference Mounting Angles

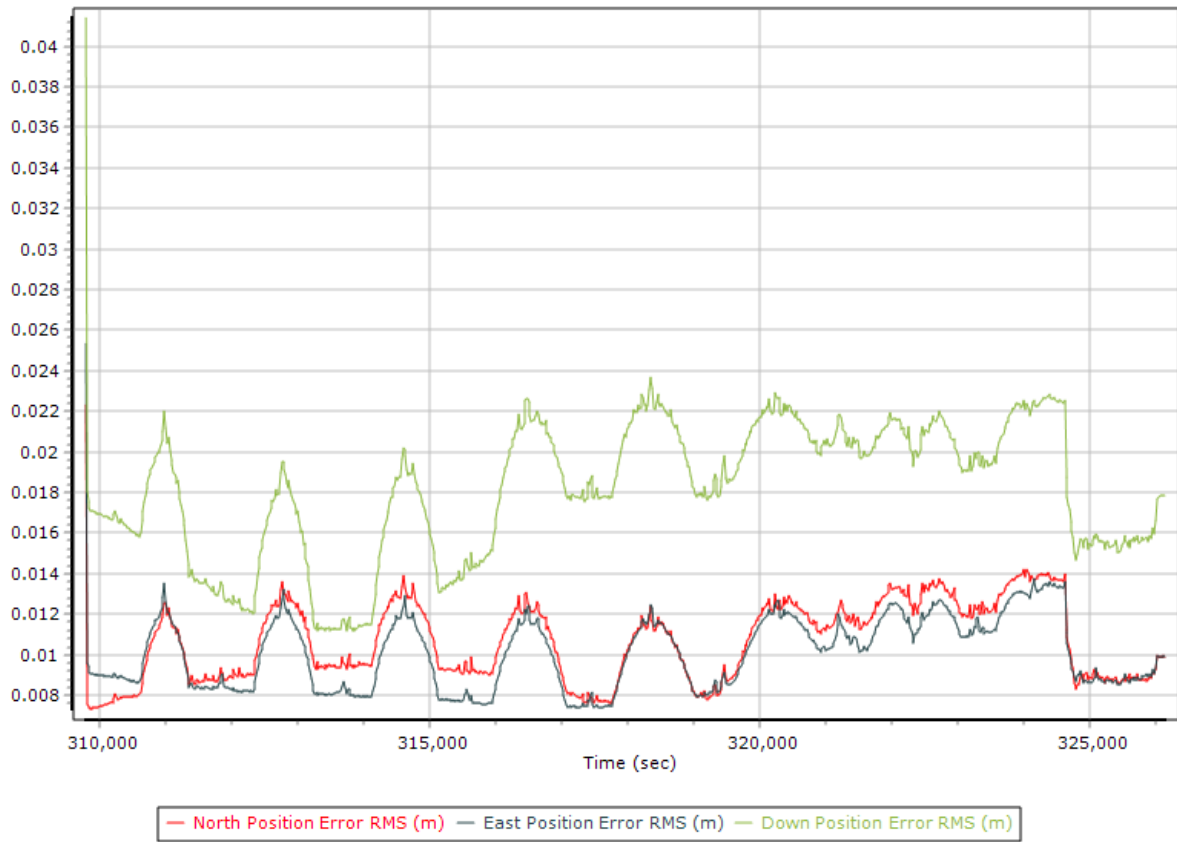
X:

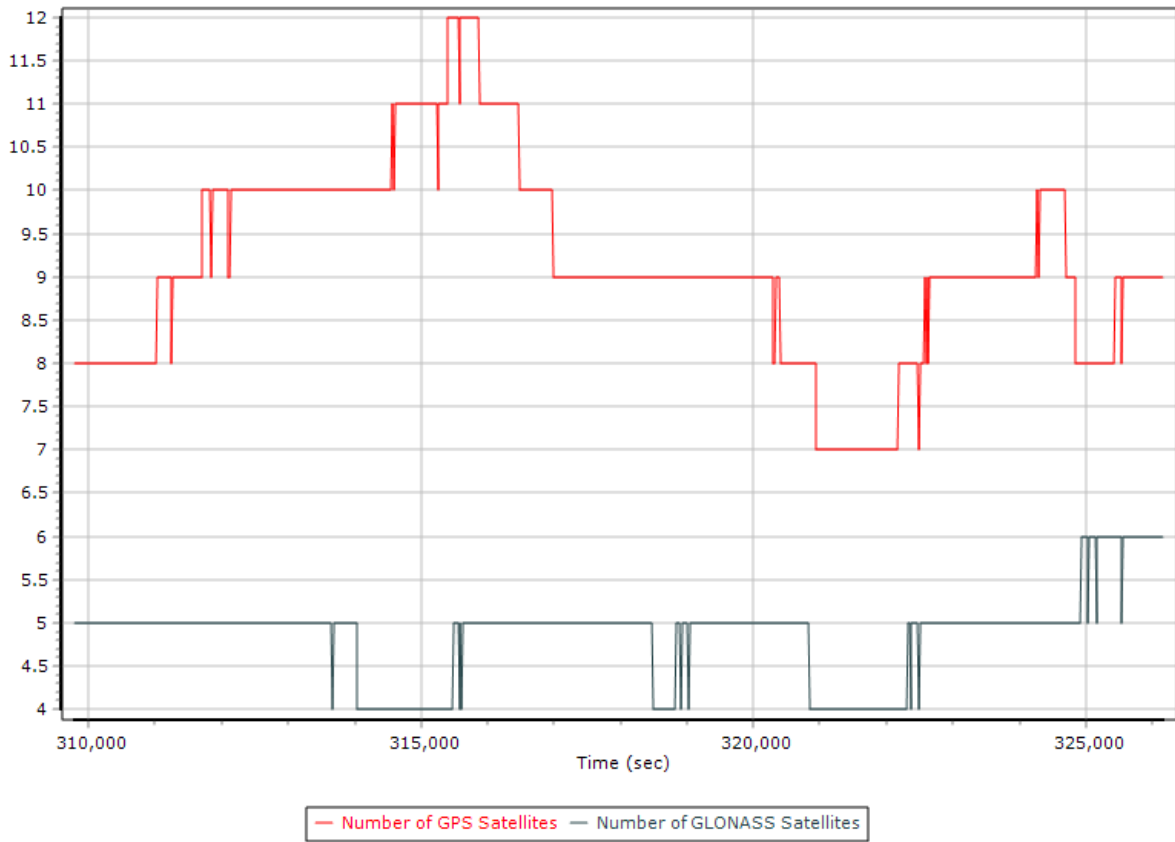
Y:

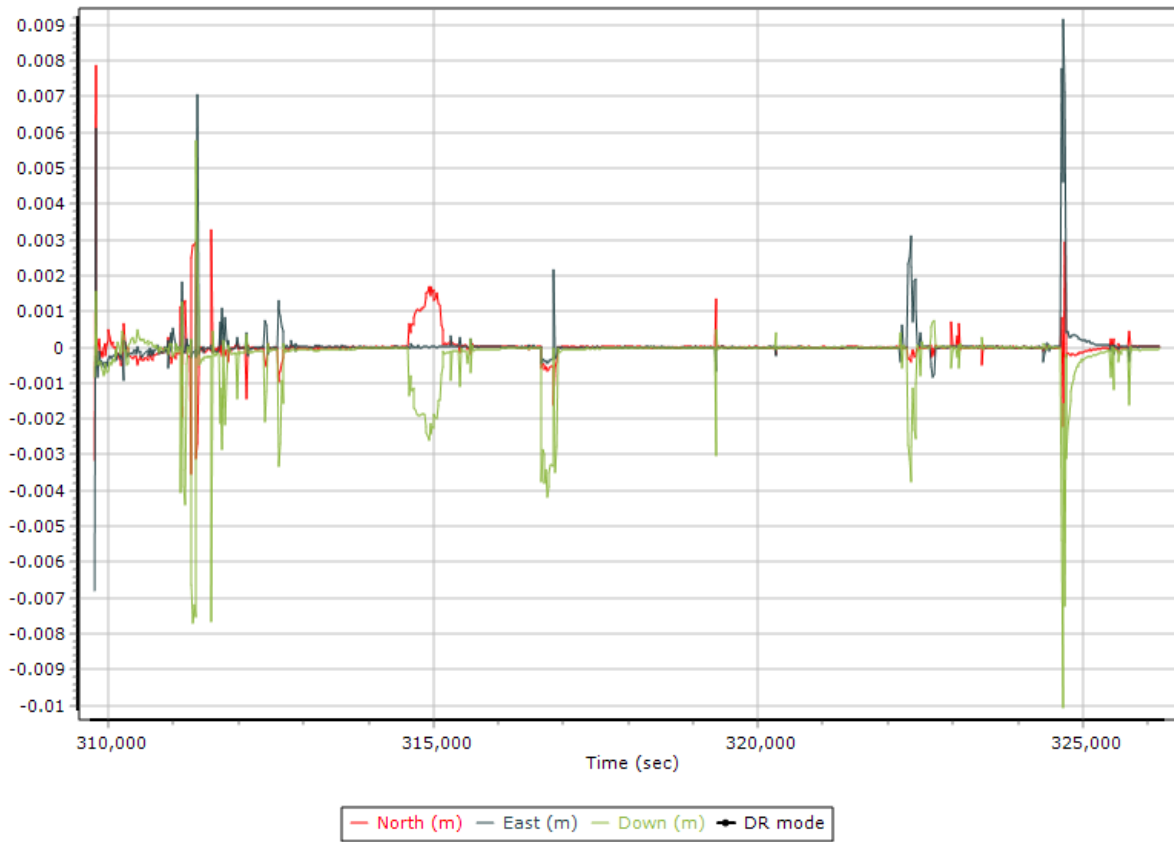
Z:

OK Cancel









Project Settings [X]

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

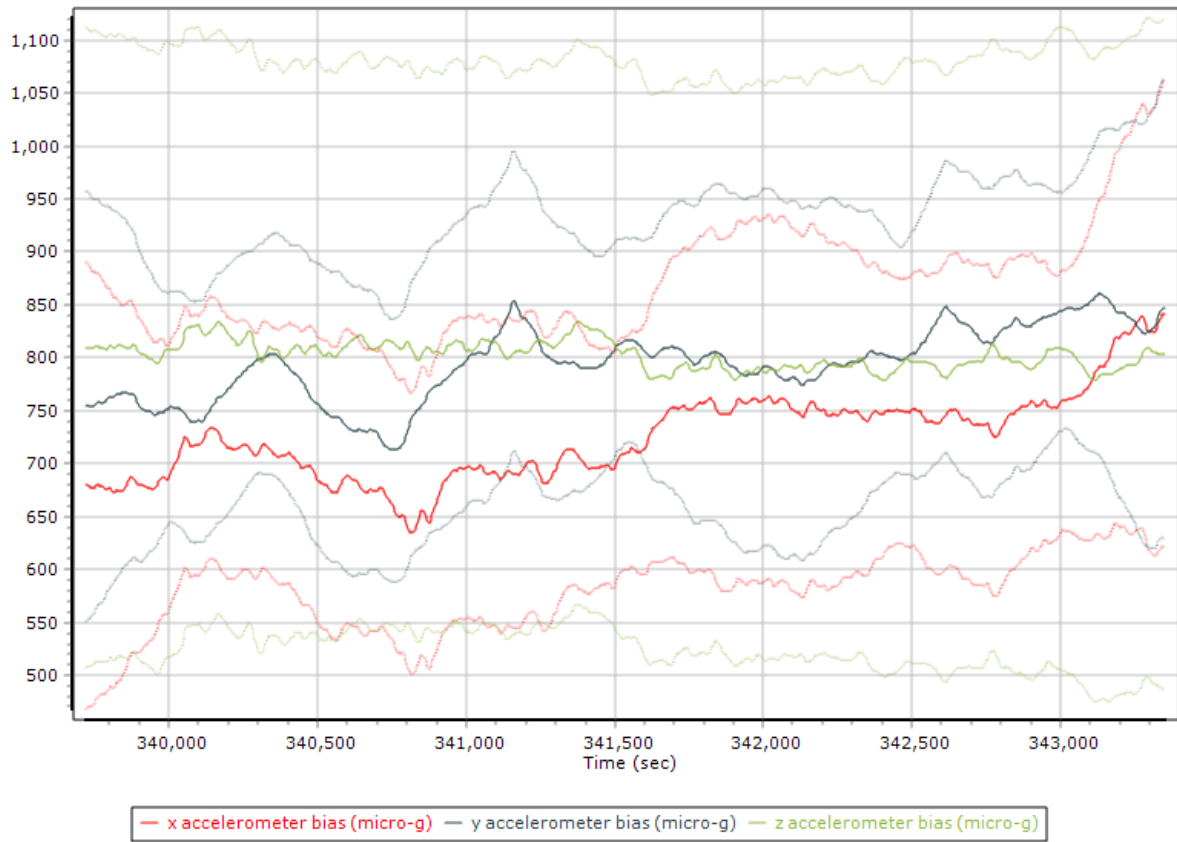
Timing

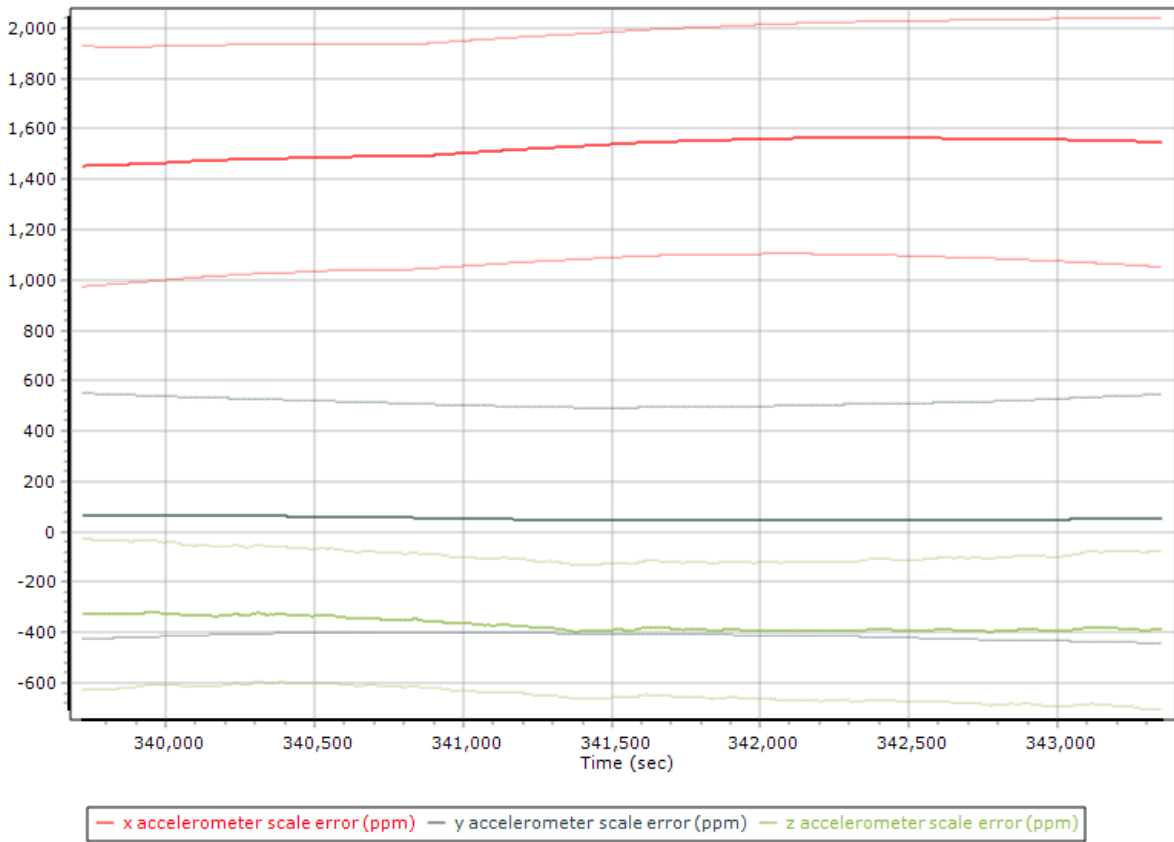
Start: 309792.108
 End: 326177.000
 Entire time interval
 Seconds of start week
 UTC Offset: 18.000

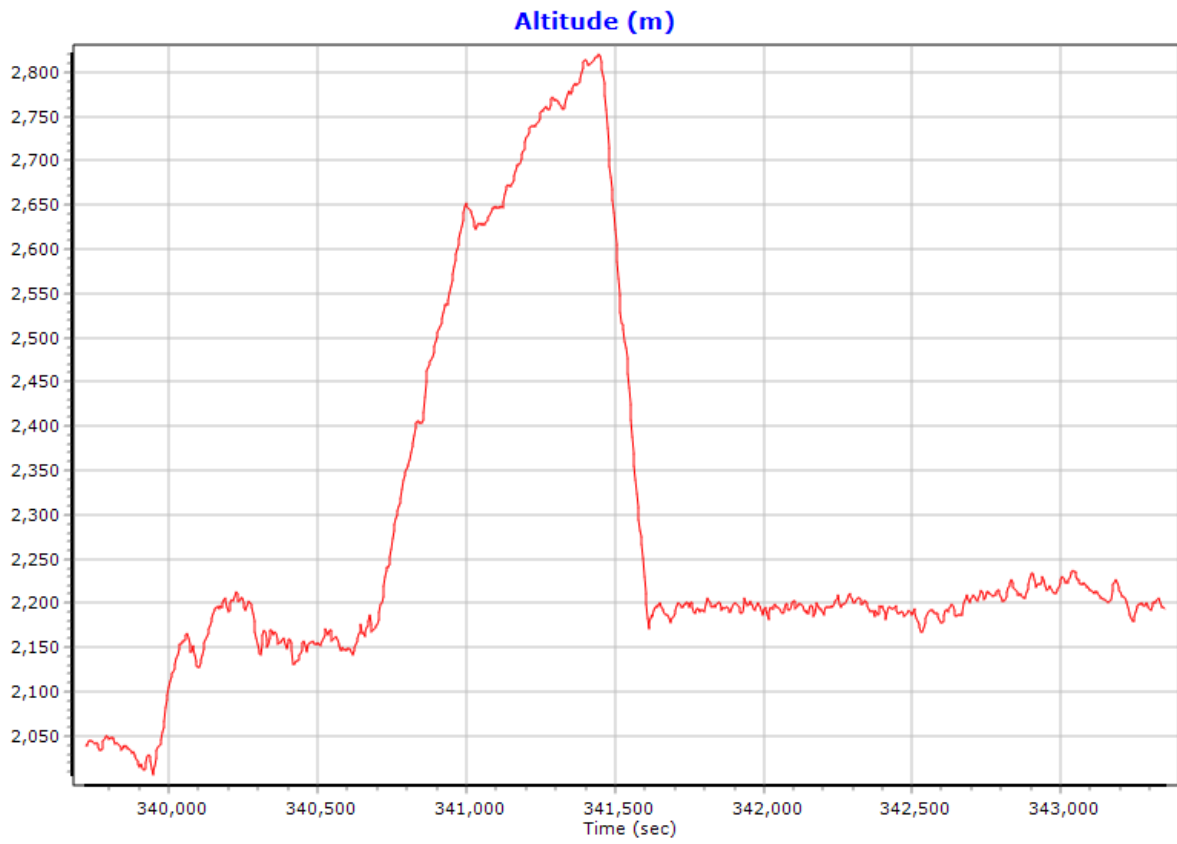
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

OK Cancel

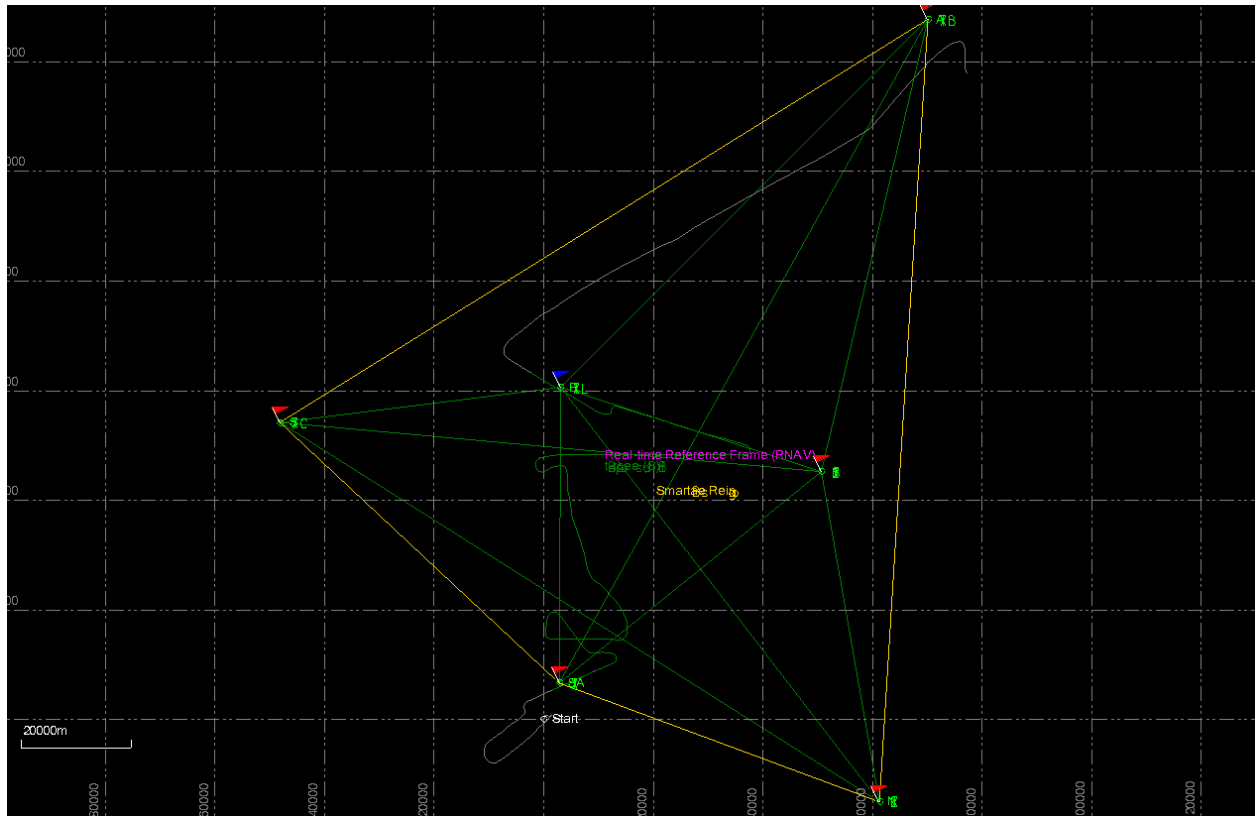
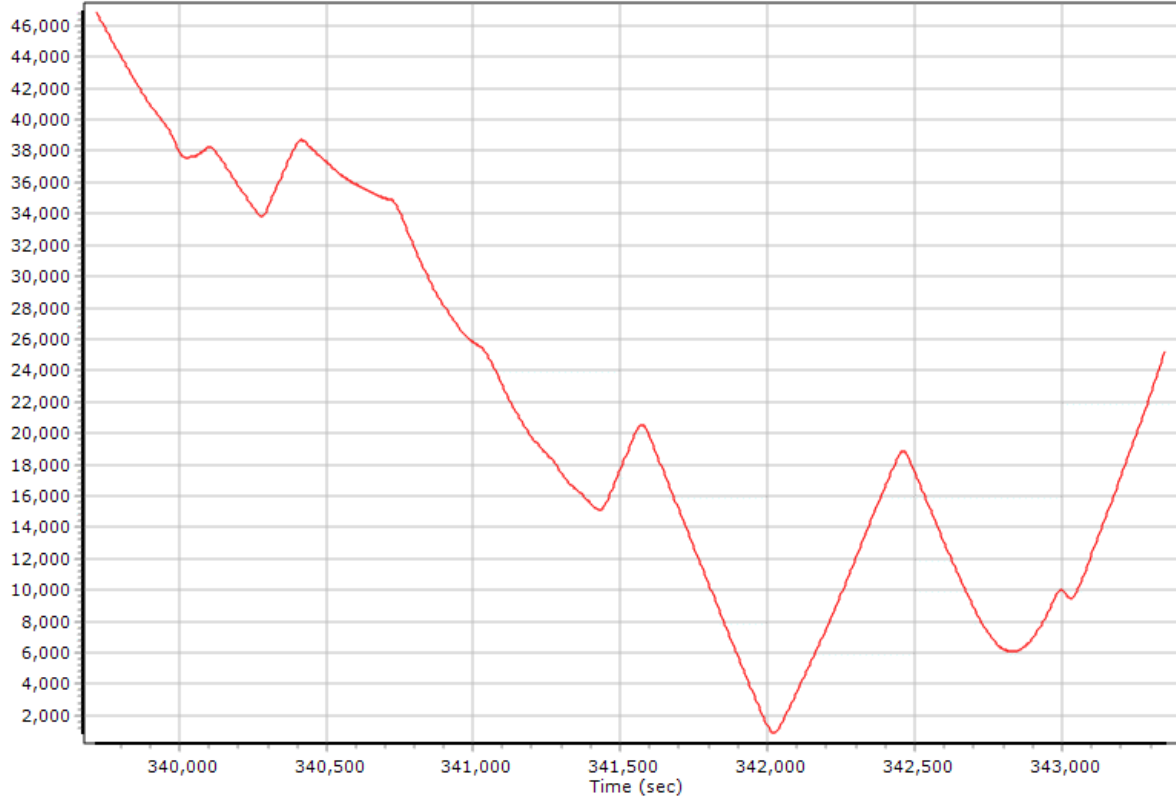
UNB18073B

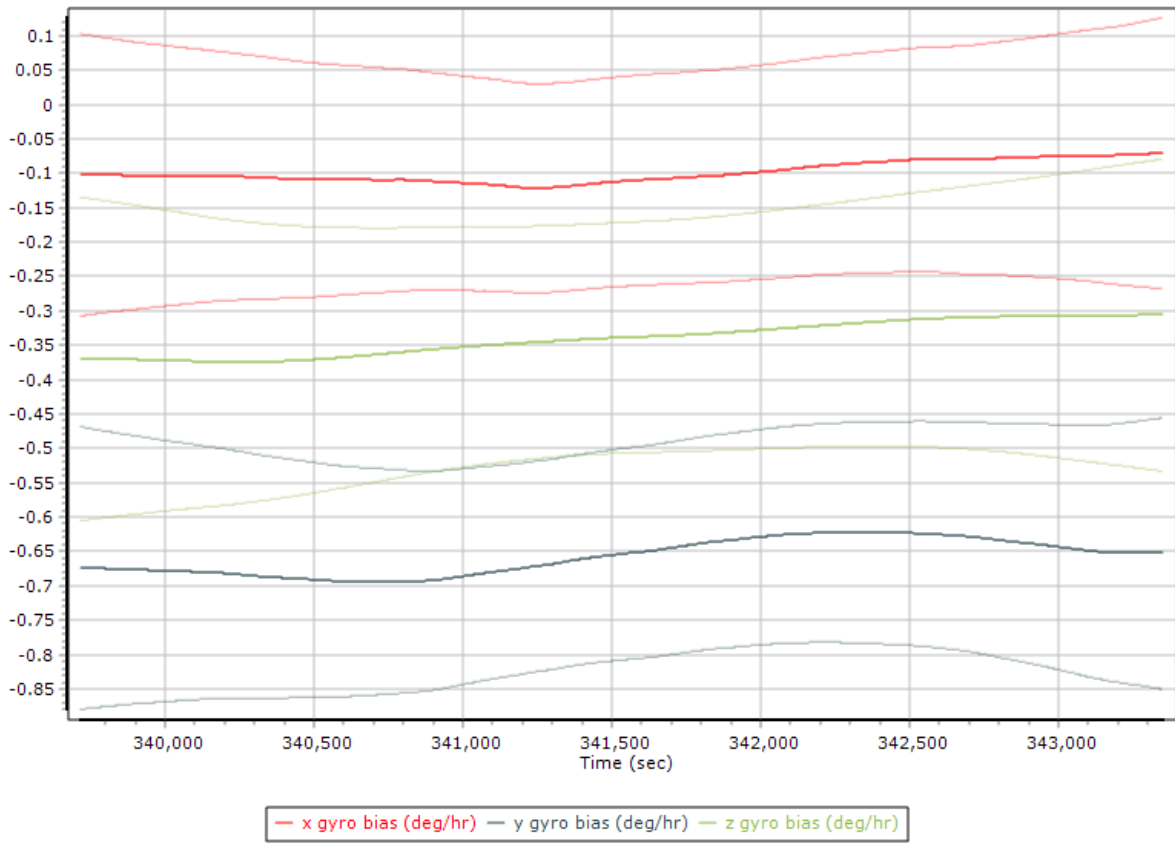


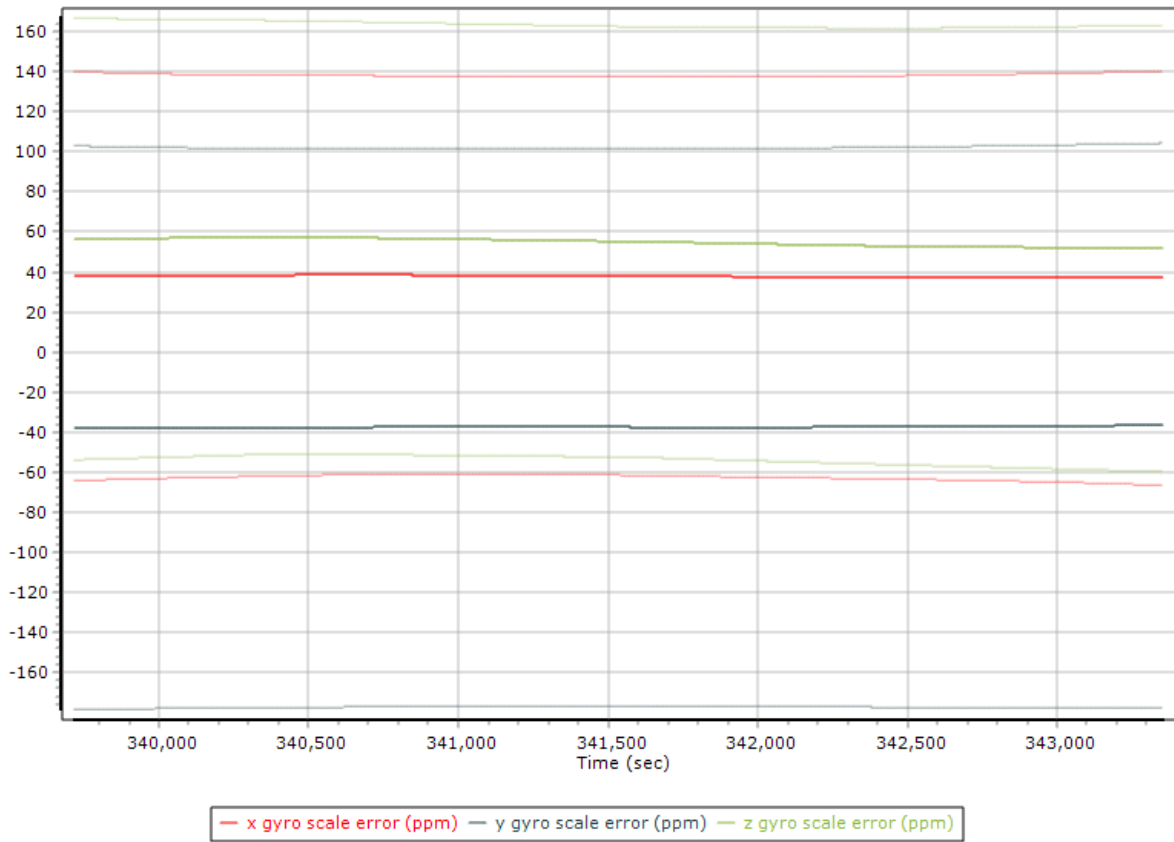




Baseline Length (m)







Project Settings [X]

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

Reference to IMU Lever Arm

X:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

Aircraft to Reference Mounting Angles

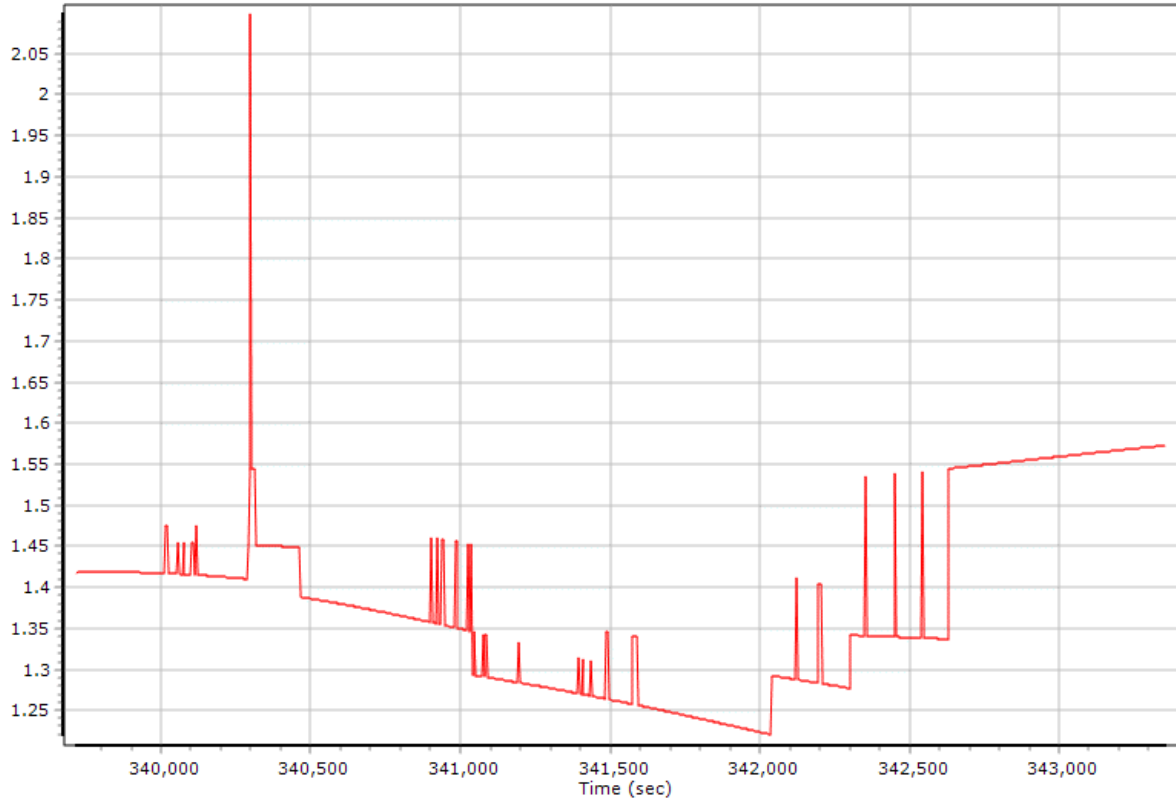
X:

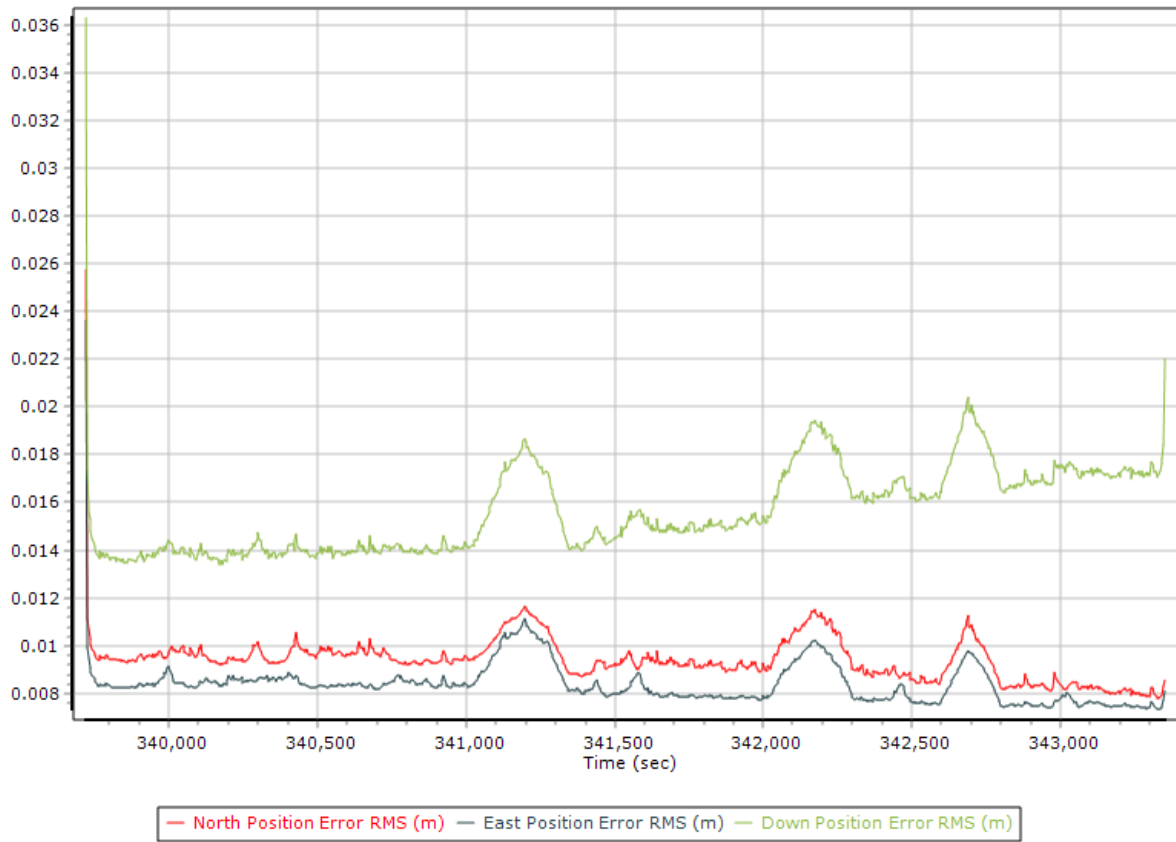
Y:

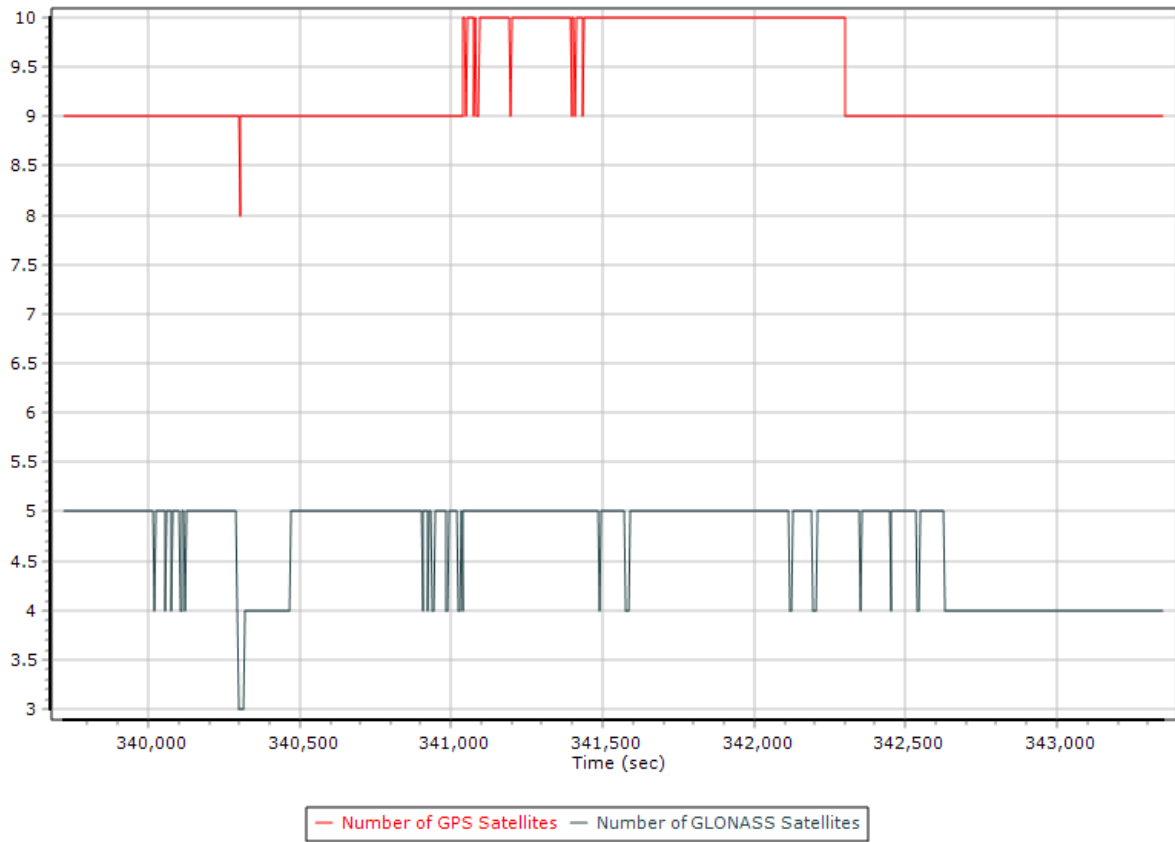
Z:

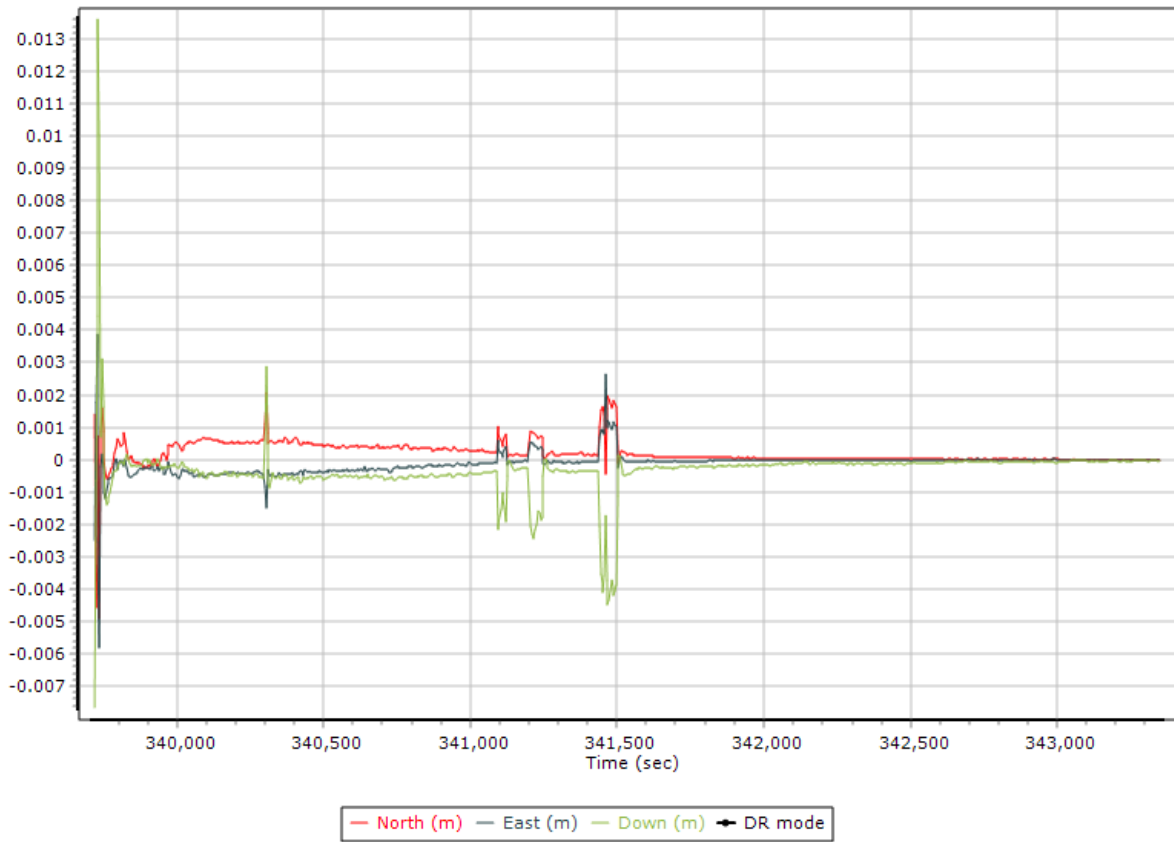
OK Cancel

PDOP









Project Settings [X]

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

Timing

Start: 339716.962
 End: 343355.095

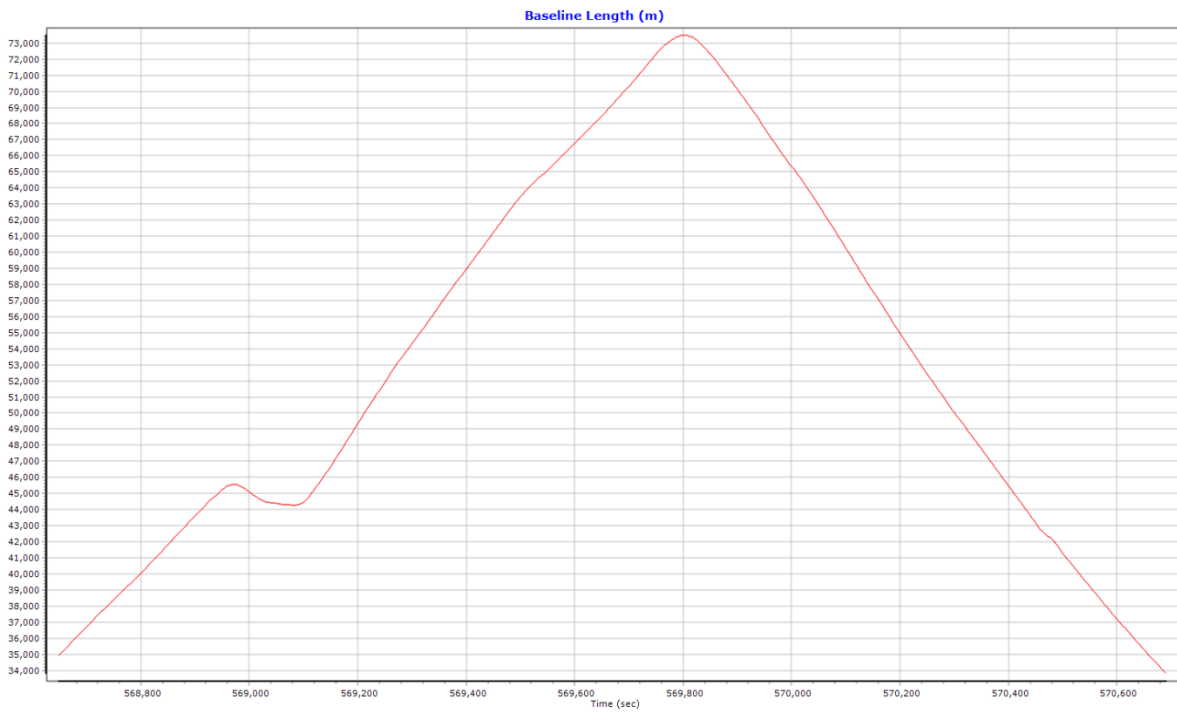
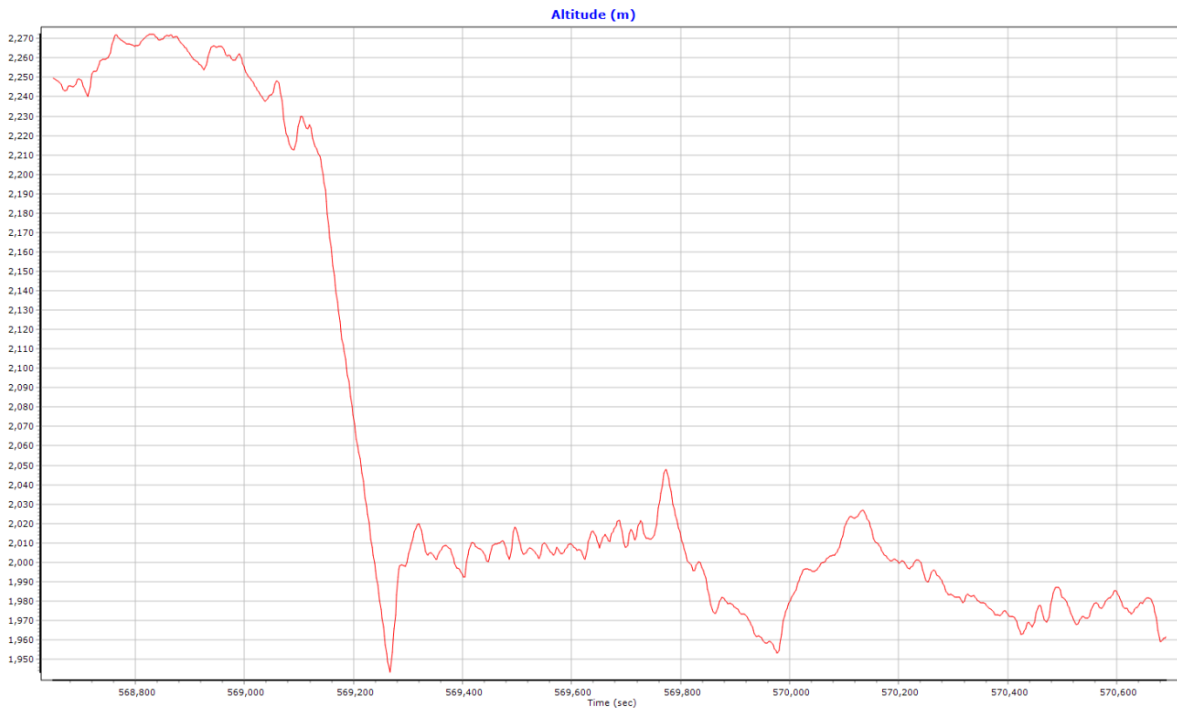
Entire time interval
 Seconds of start week

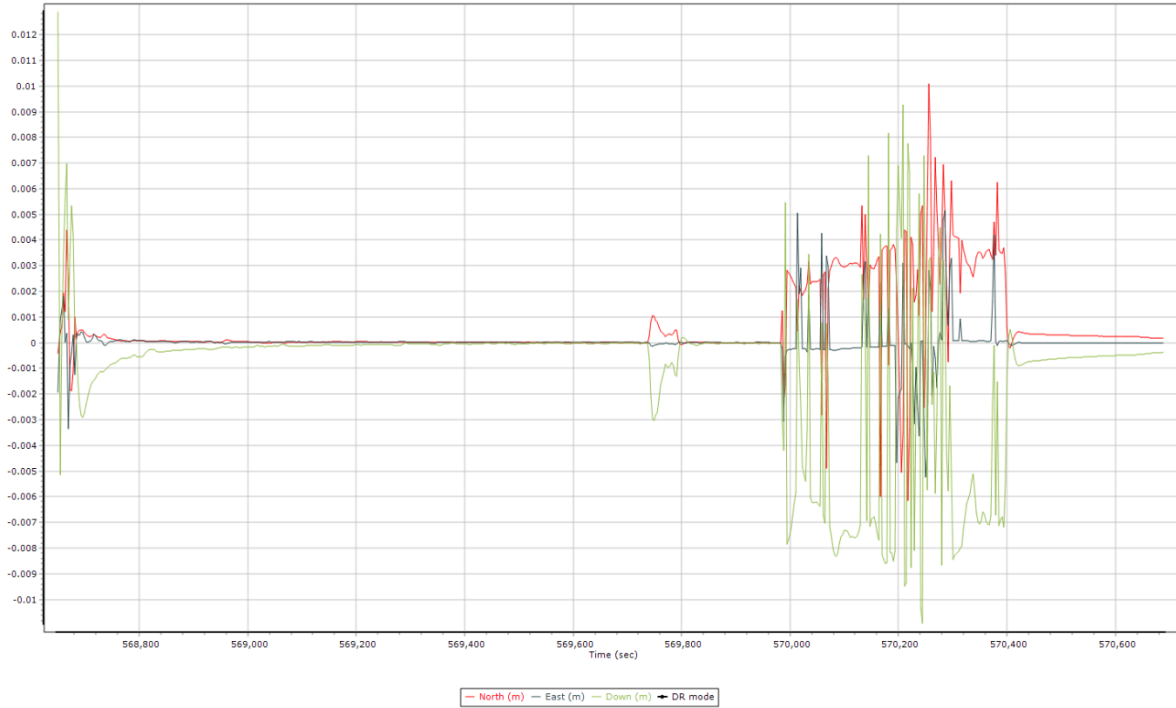
UTC Offset: 18.000

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

OK Cancel

UNB18076A





Project Settings

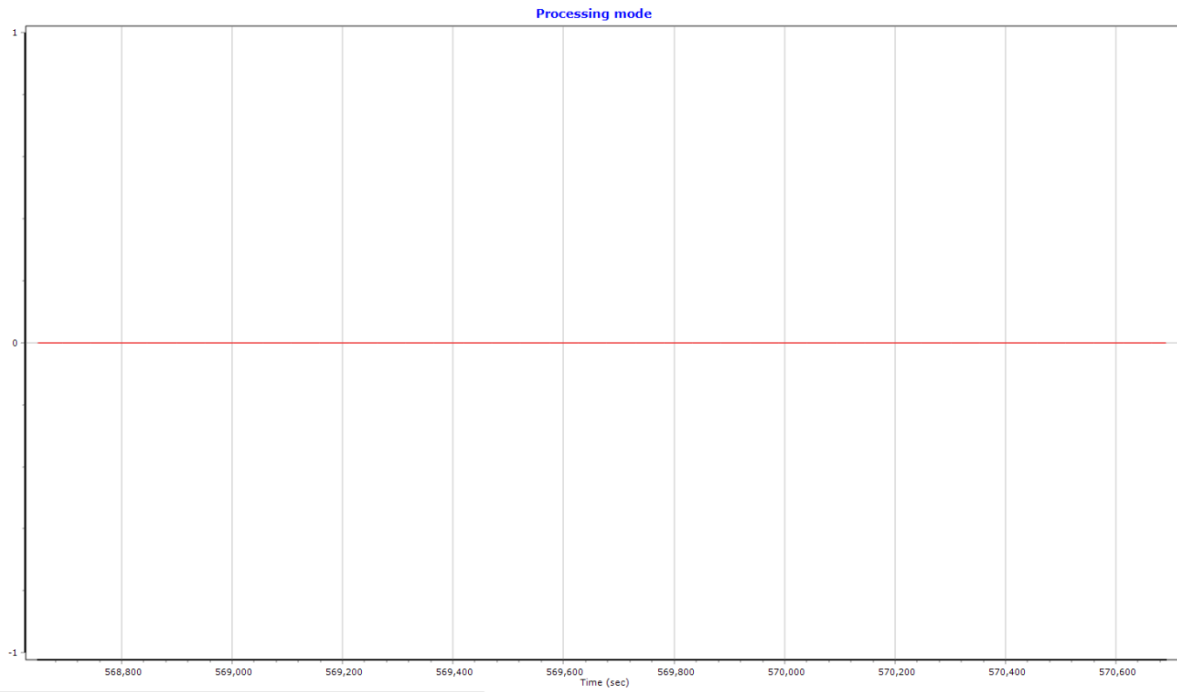
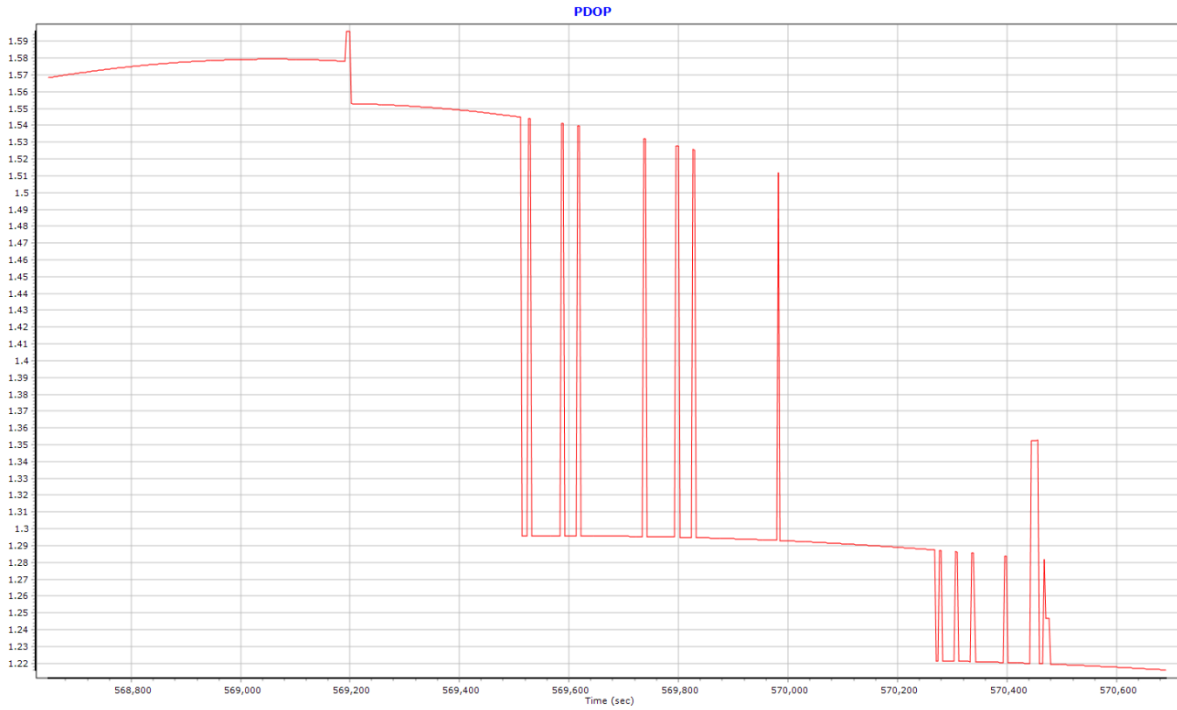
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

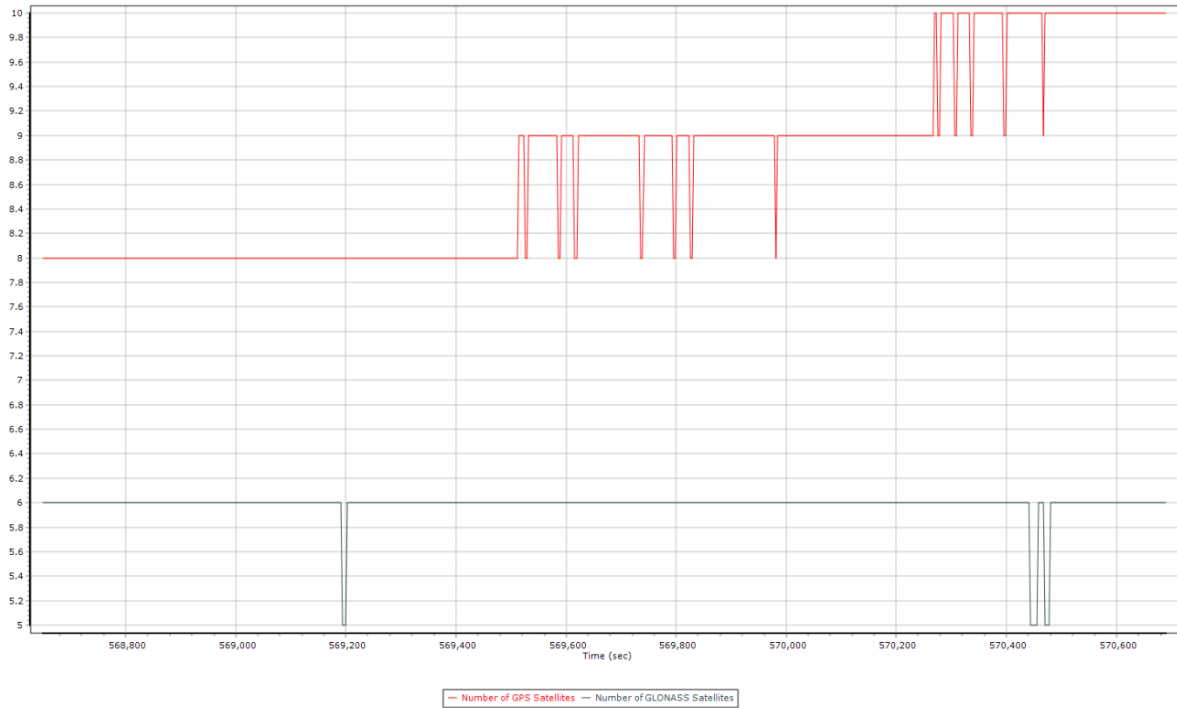
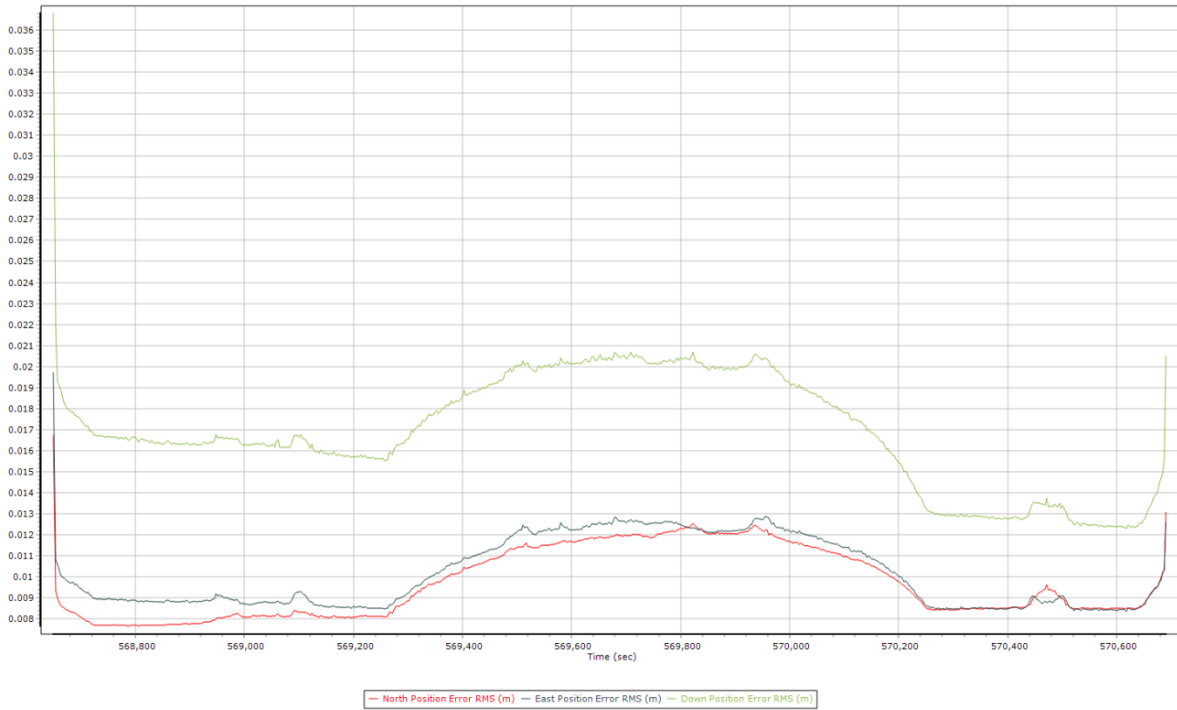
Reference to IMU Lever Arm	Reference to IMU Mounting Angles
X: 0.034 m	X: 0.000 deg
Y: 0.018 m	Y: 0.000 deg
Z: -0.155 m	Z: 0.000 deg

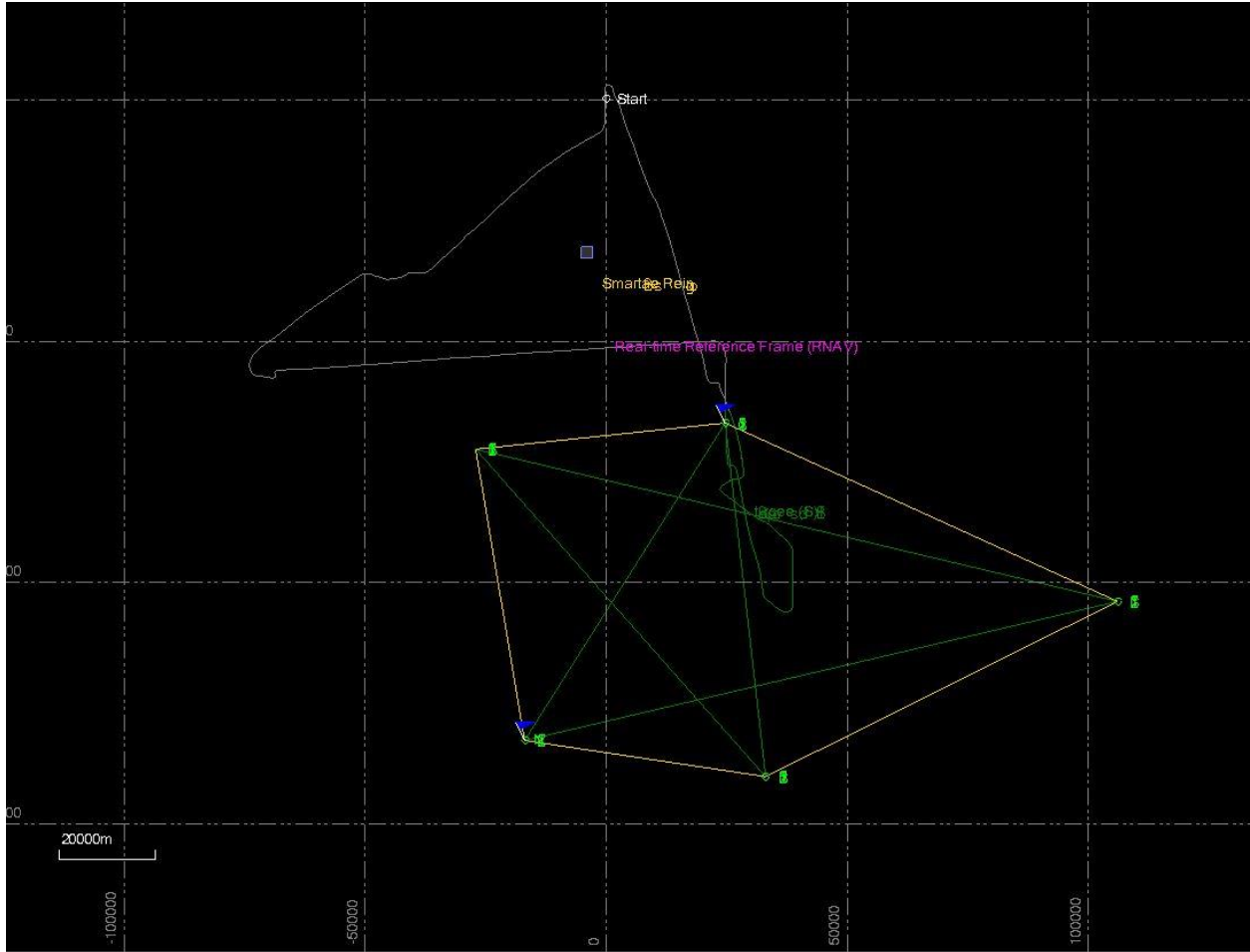
Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.105 m	X: 0.000 deg
Y: -0.052 m	Y: 0.000 deg
Z: -0.964 m	Z: 0.000 deg

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

OK Cancel







Project Settings [X]

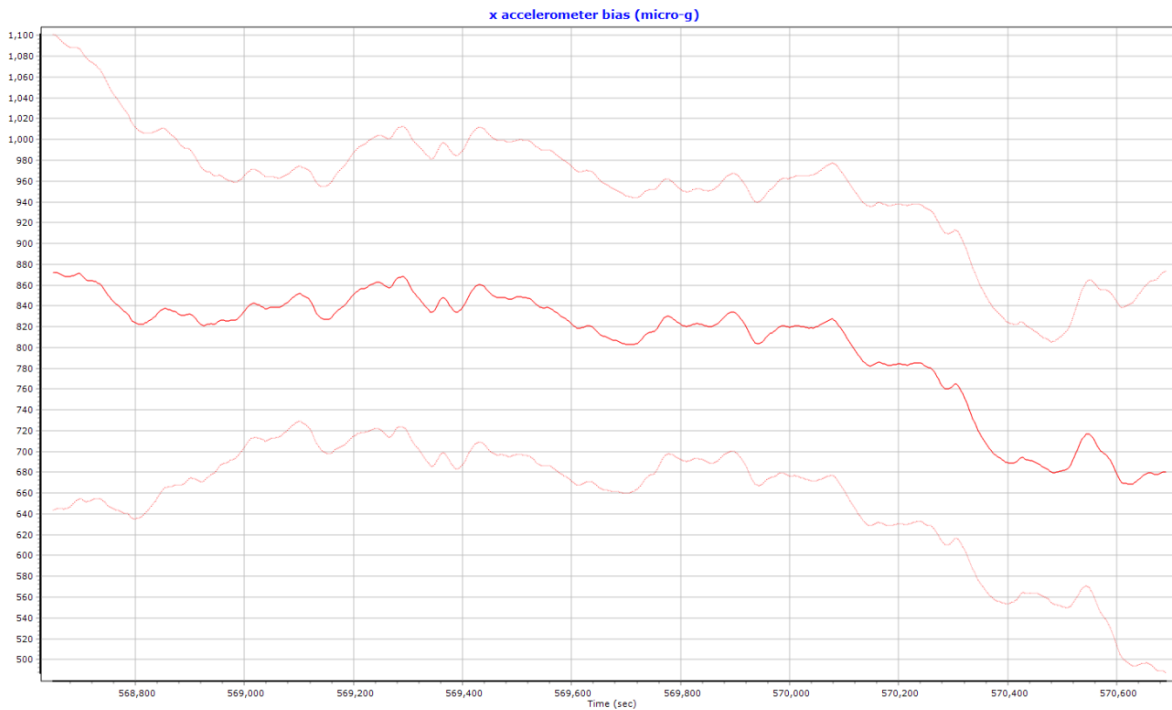
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing**
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles
- Export
- Camera
- LiDAR
- SAR

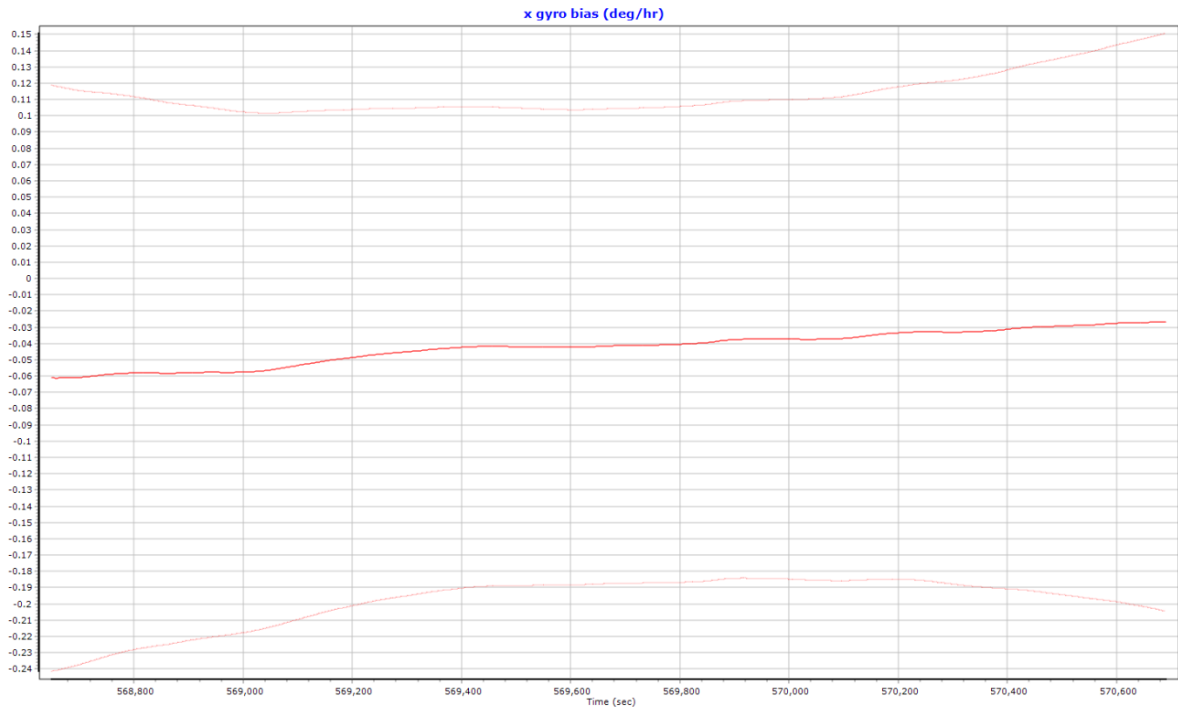
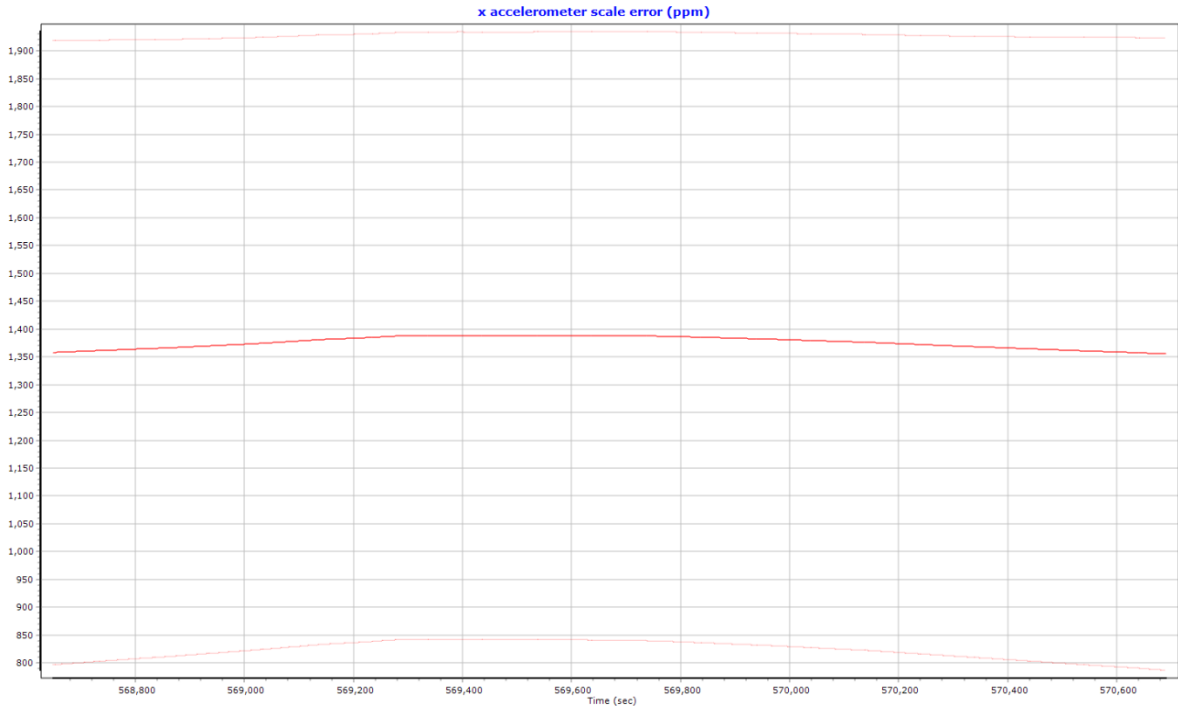
Timing

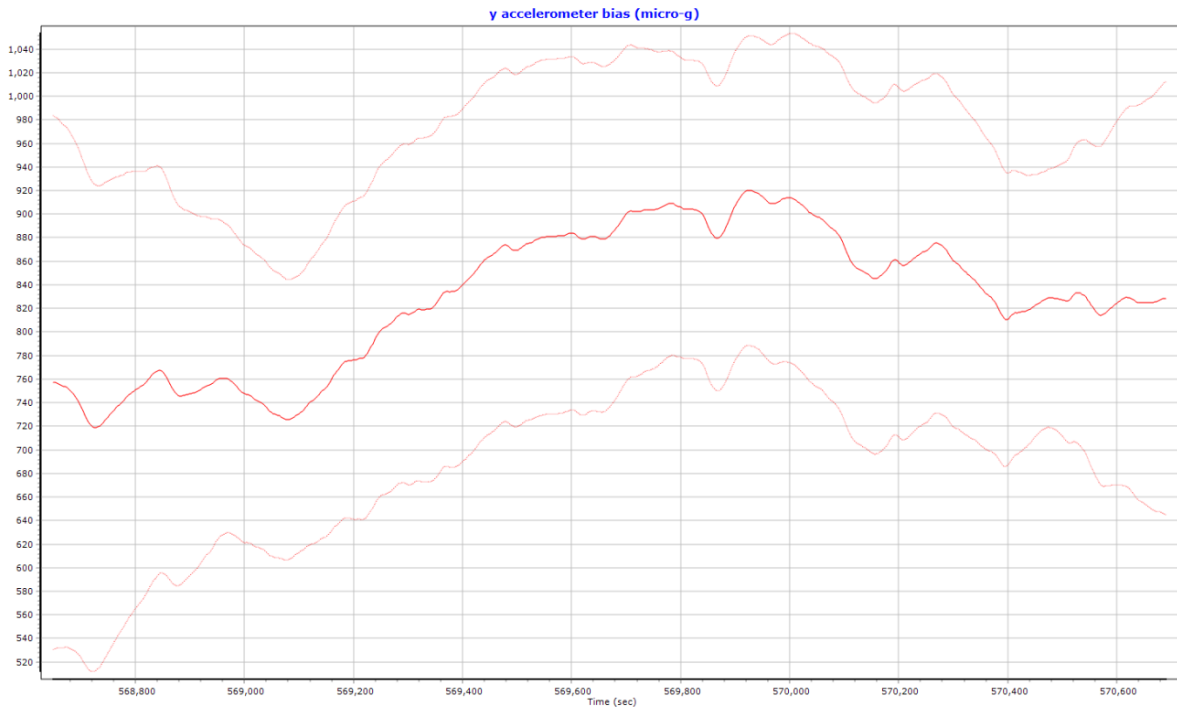
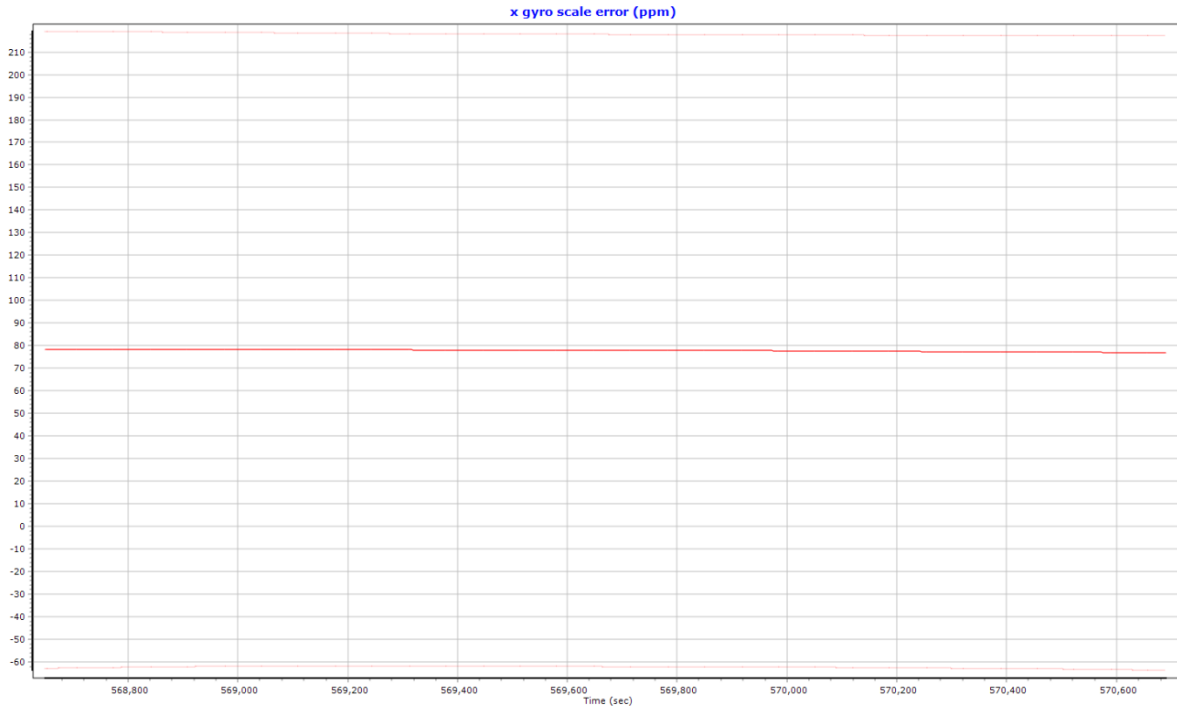
Start: 568646.344
End: 570692.419
 Entire time interval
 Seconds of start week
UTC Offset: 18.000

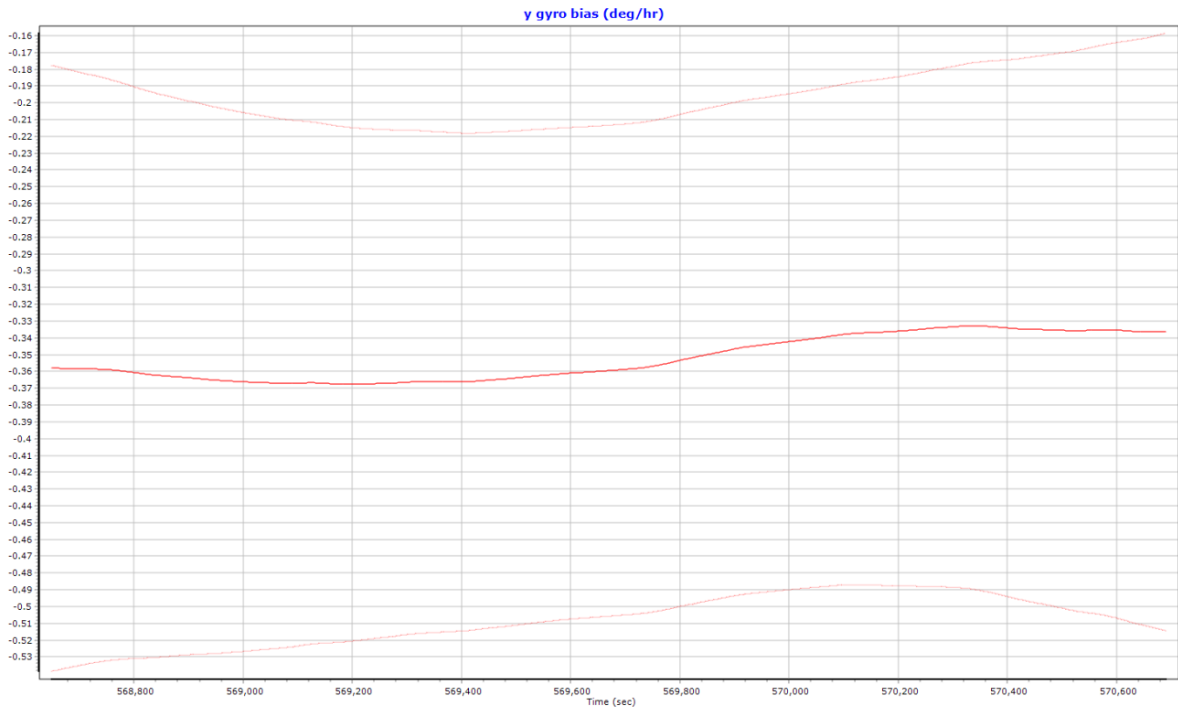
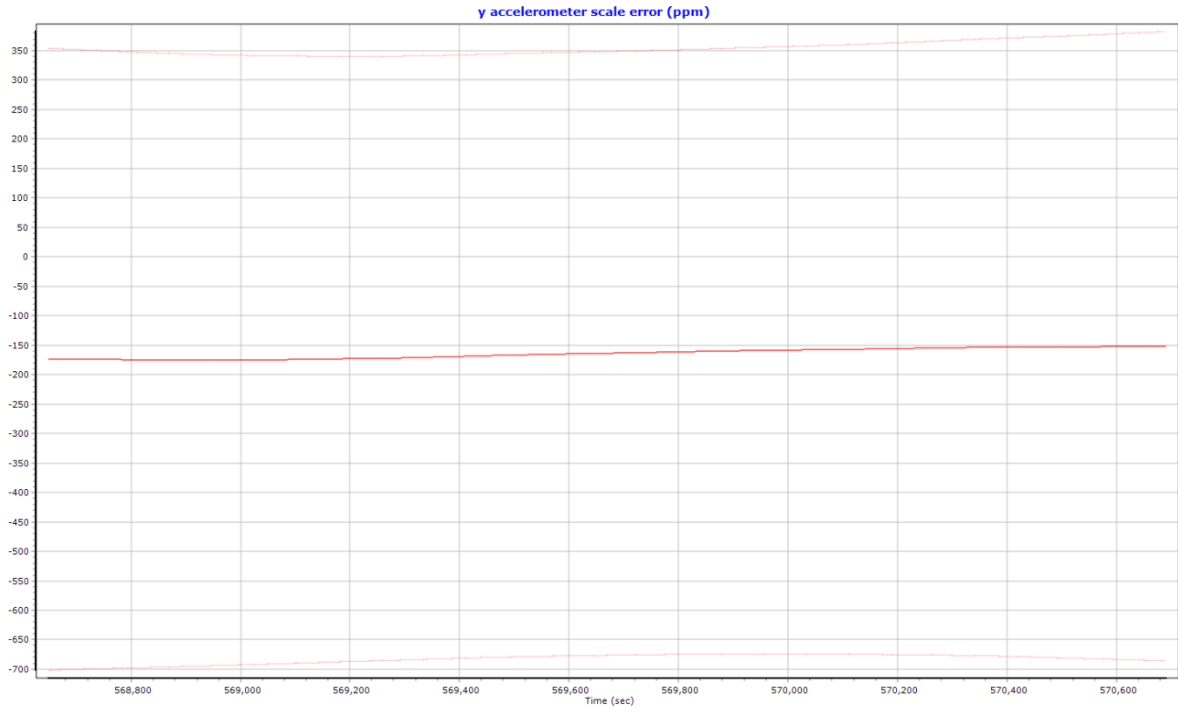
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

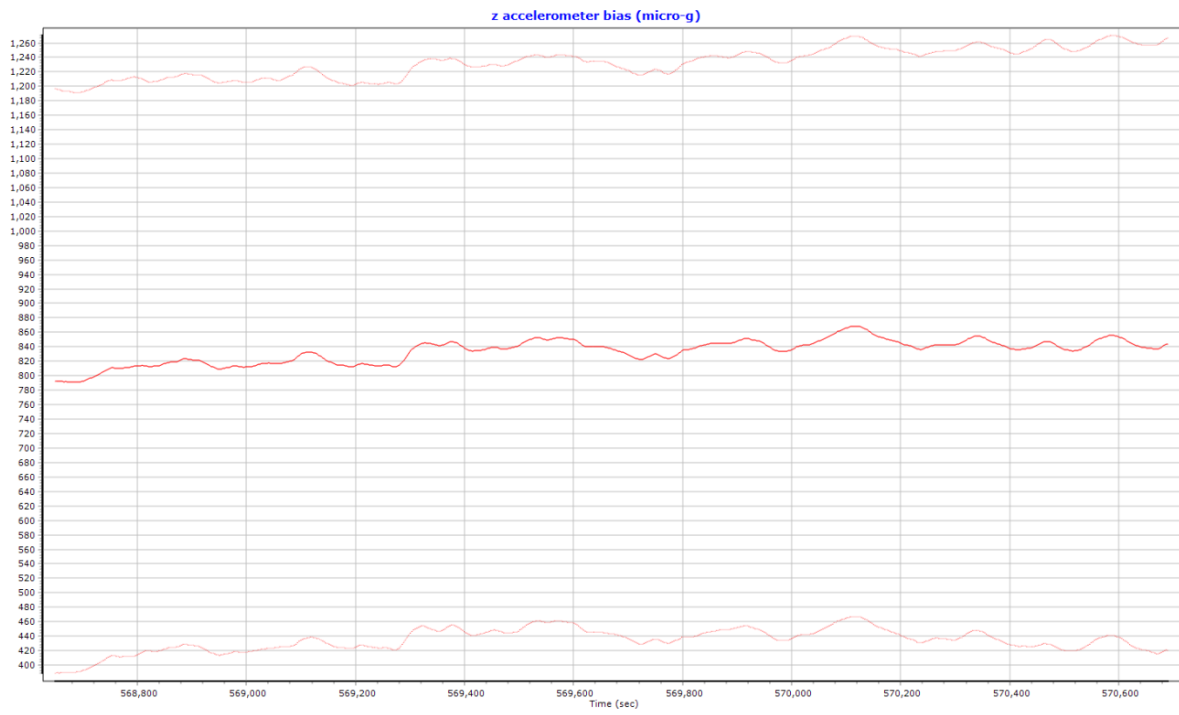
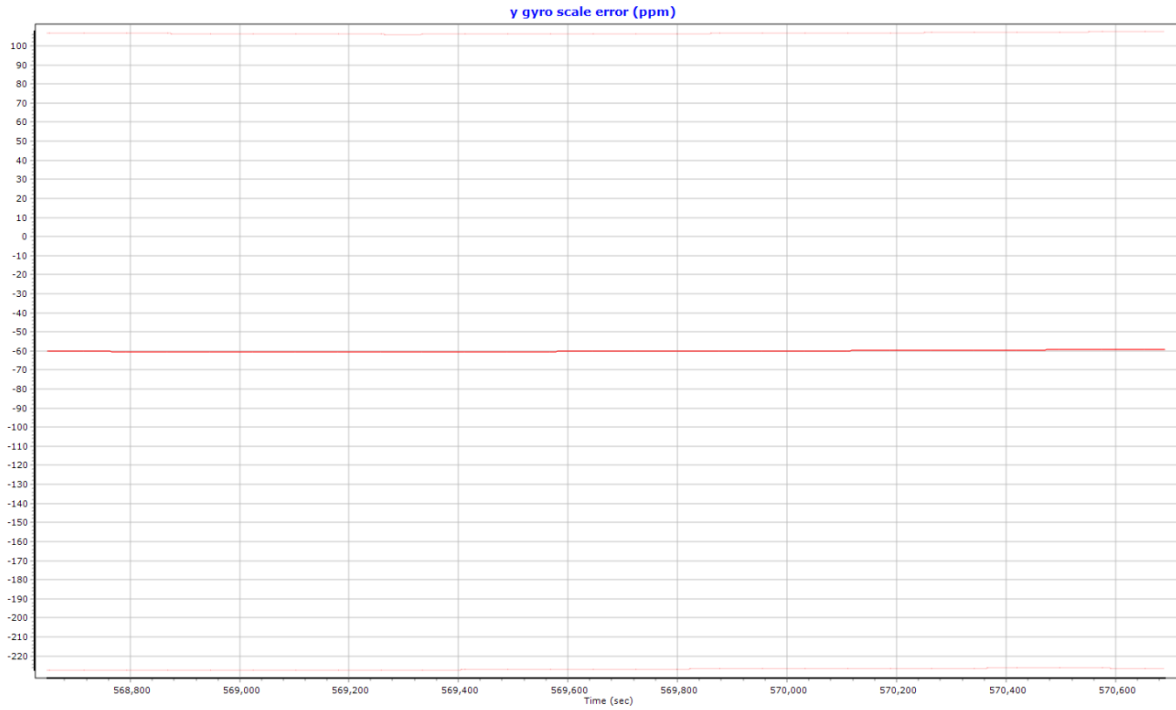
OK Cancel

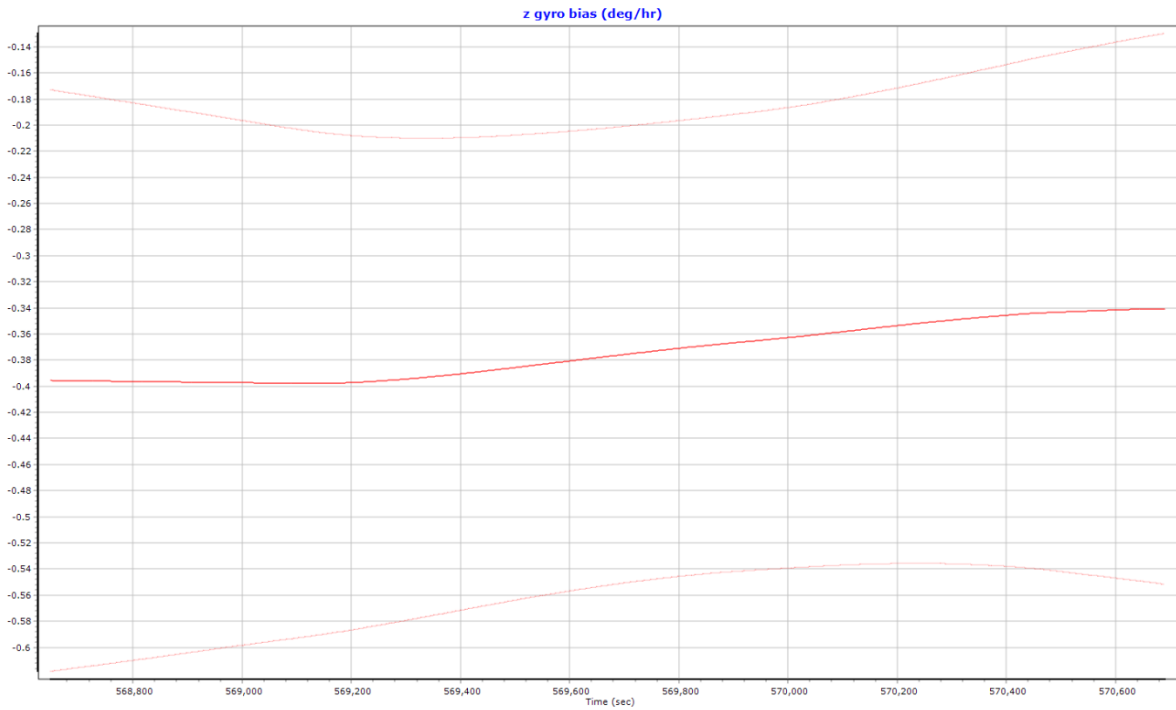
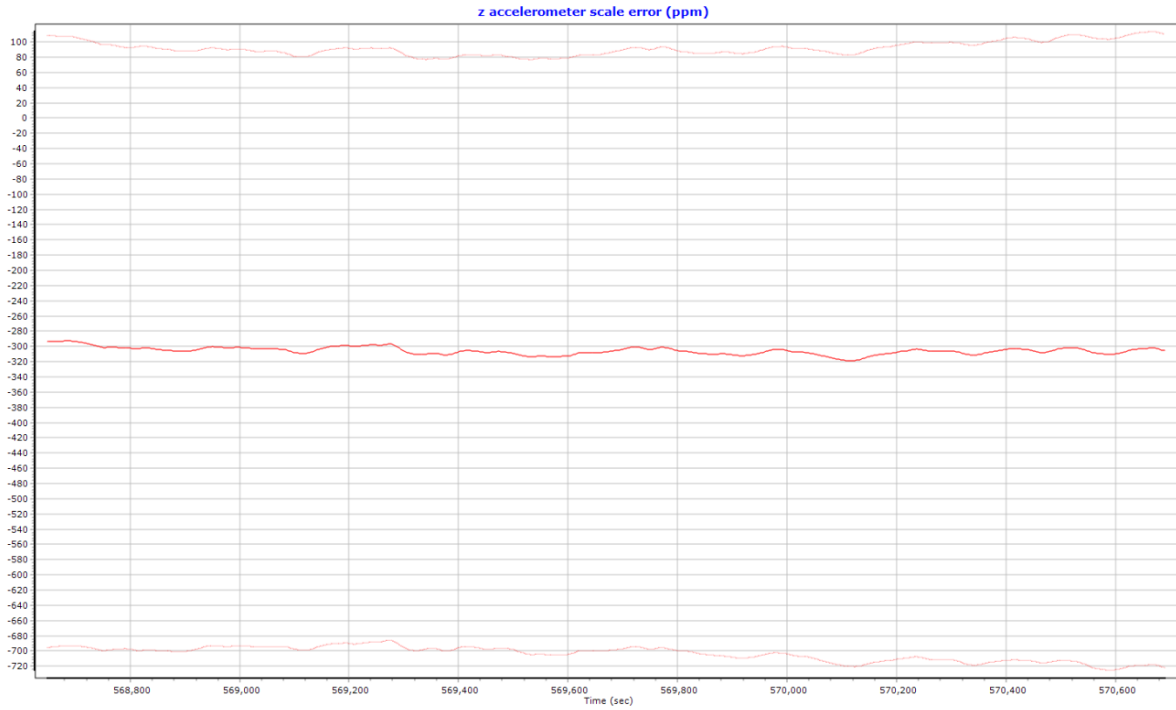


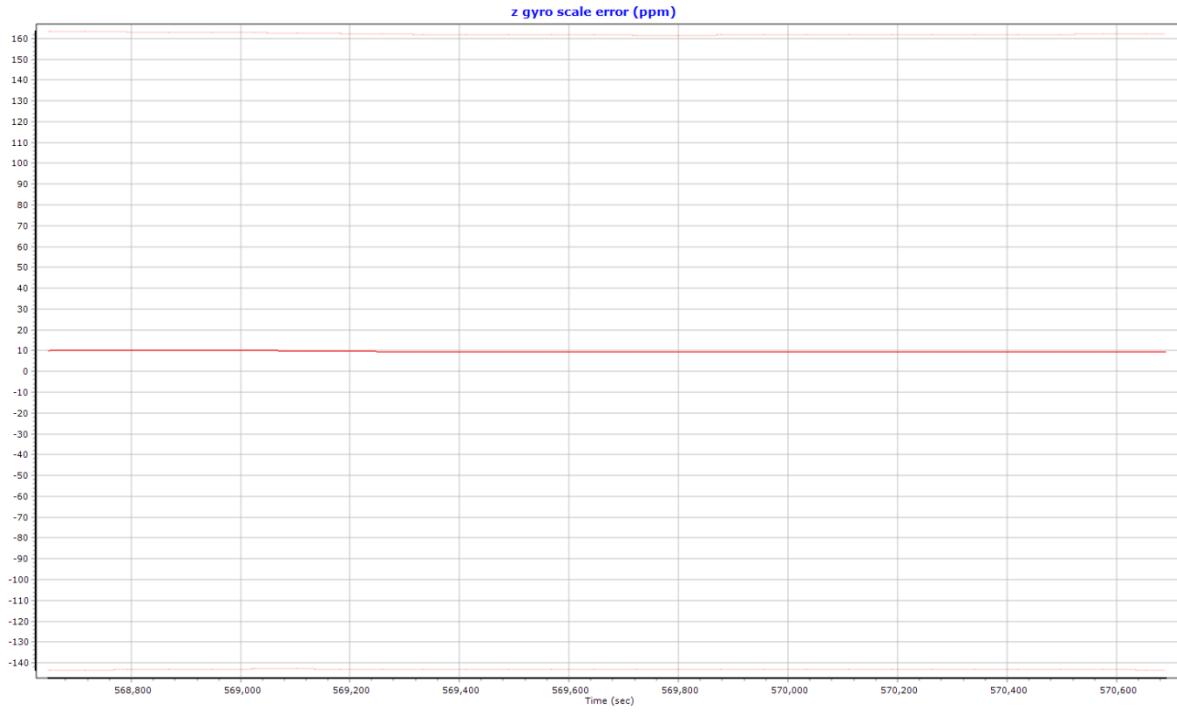




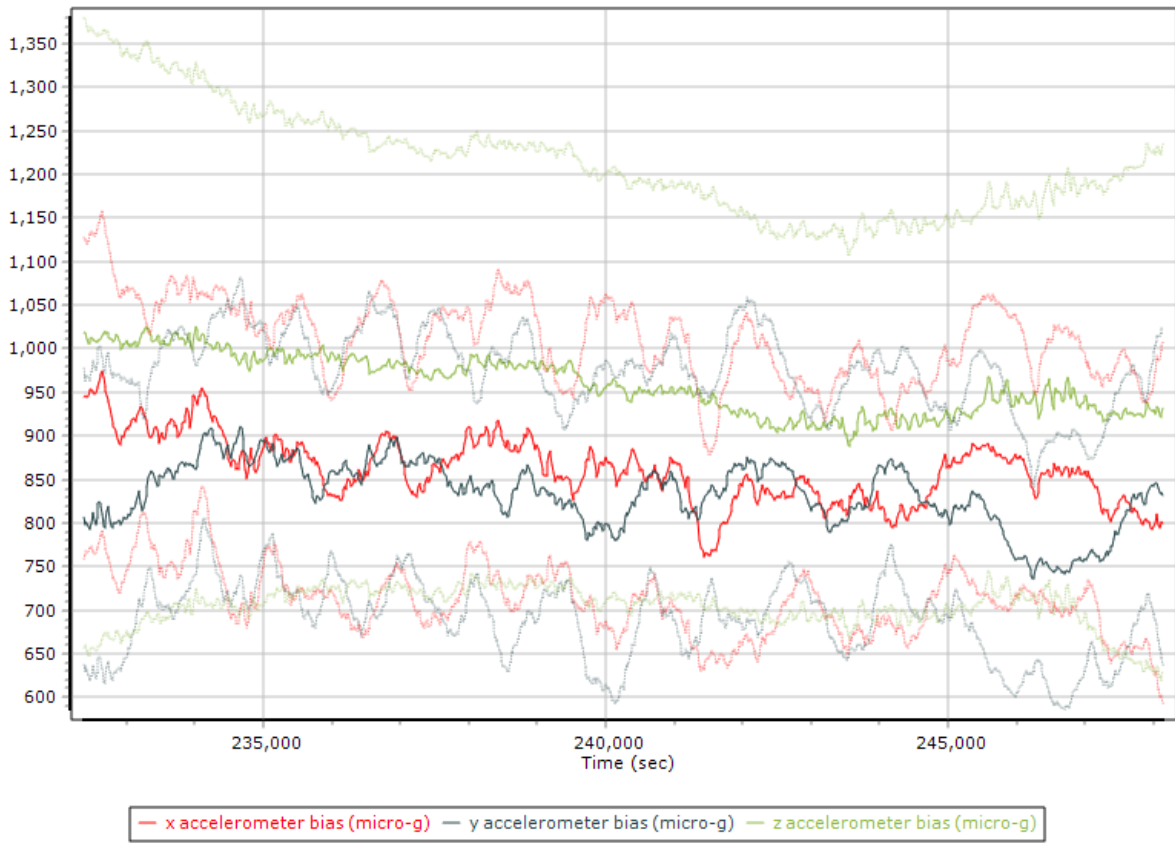


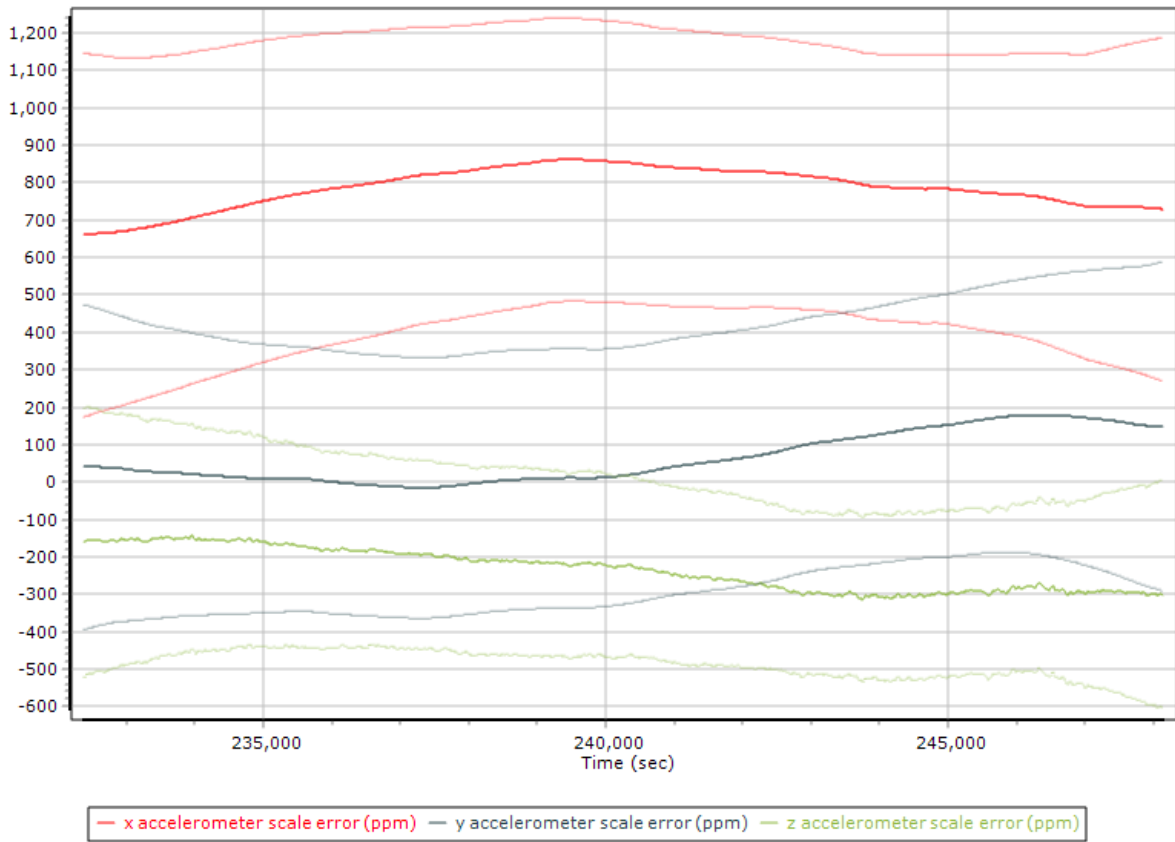


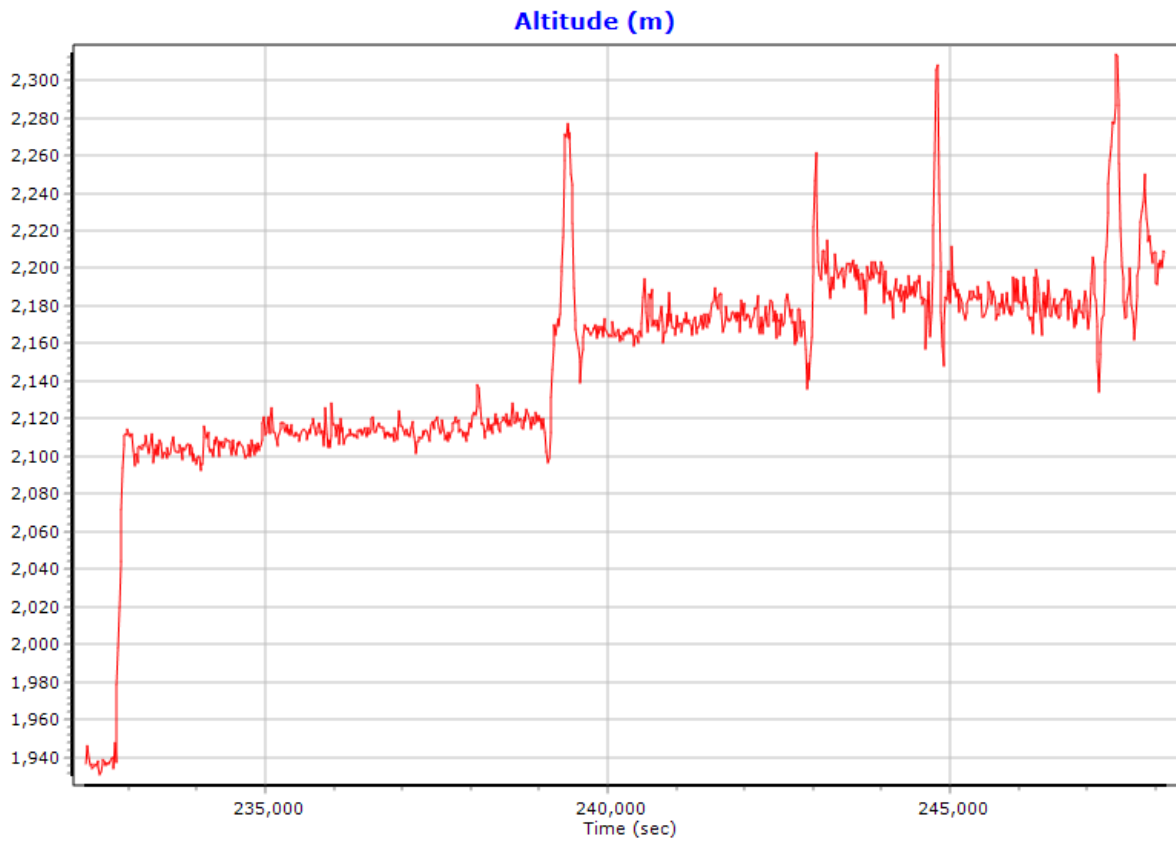


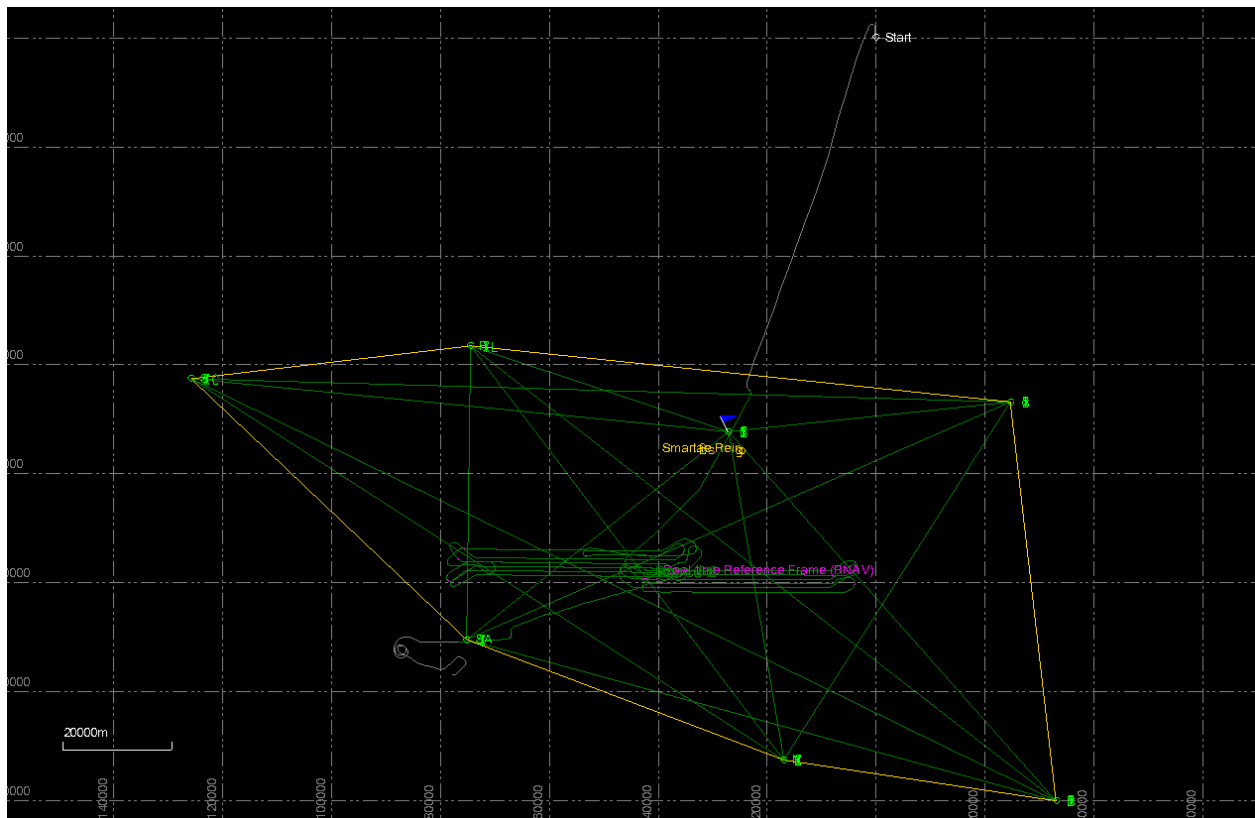
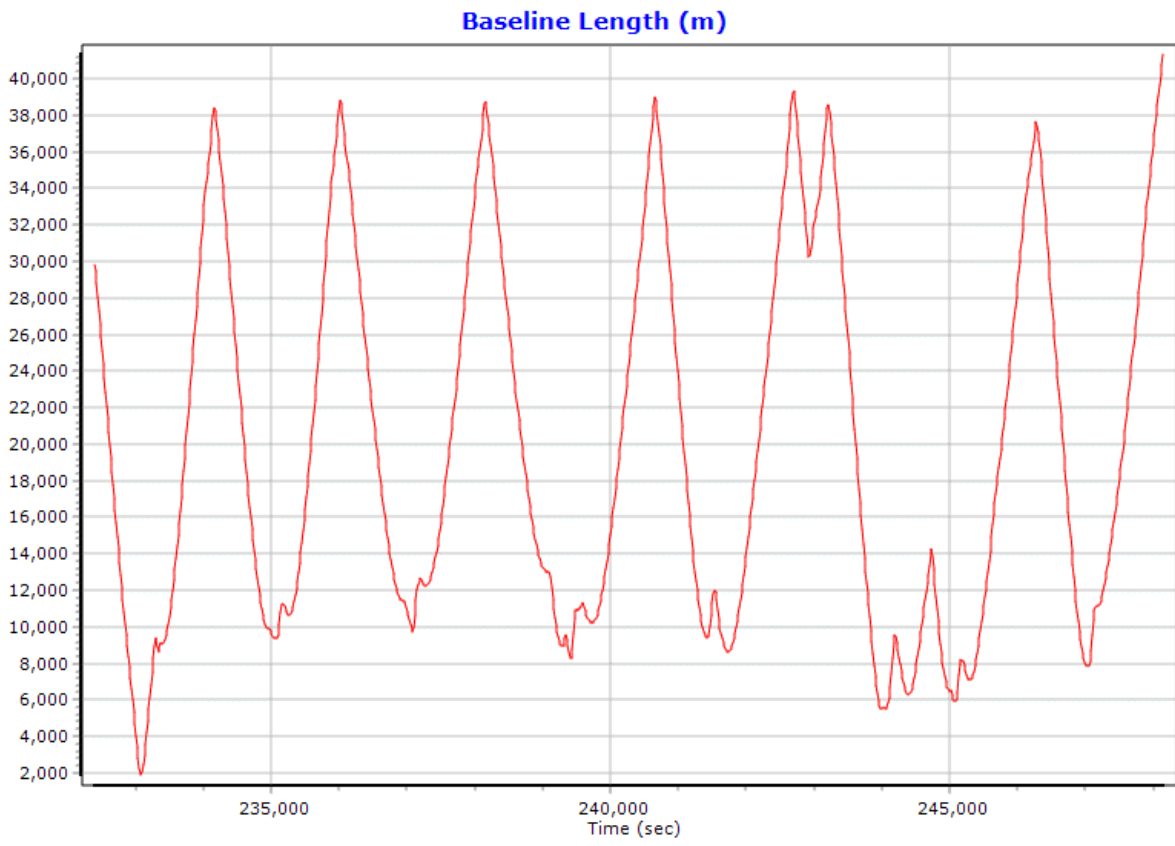


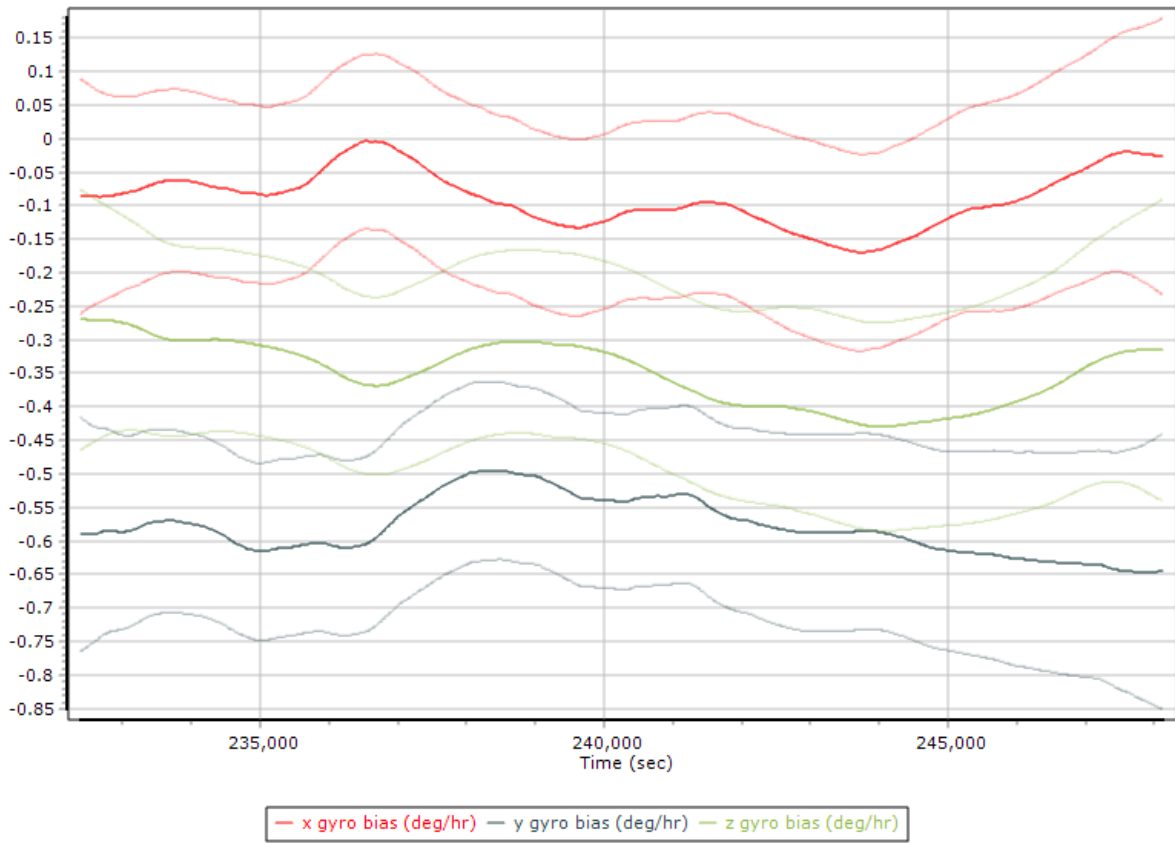
UNB18079A

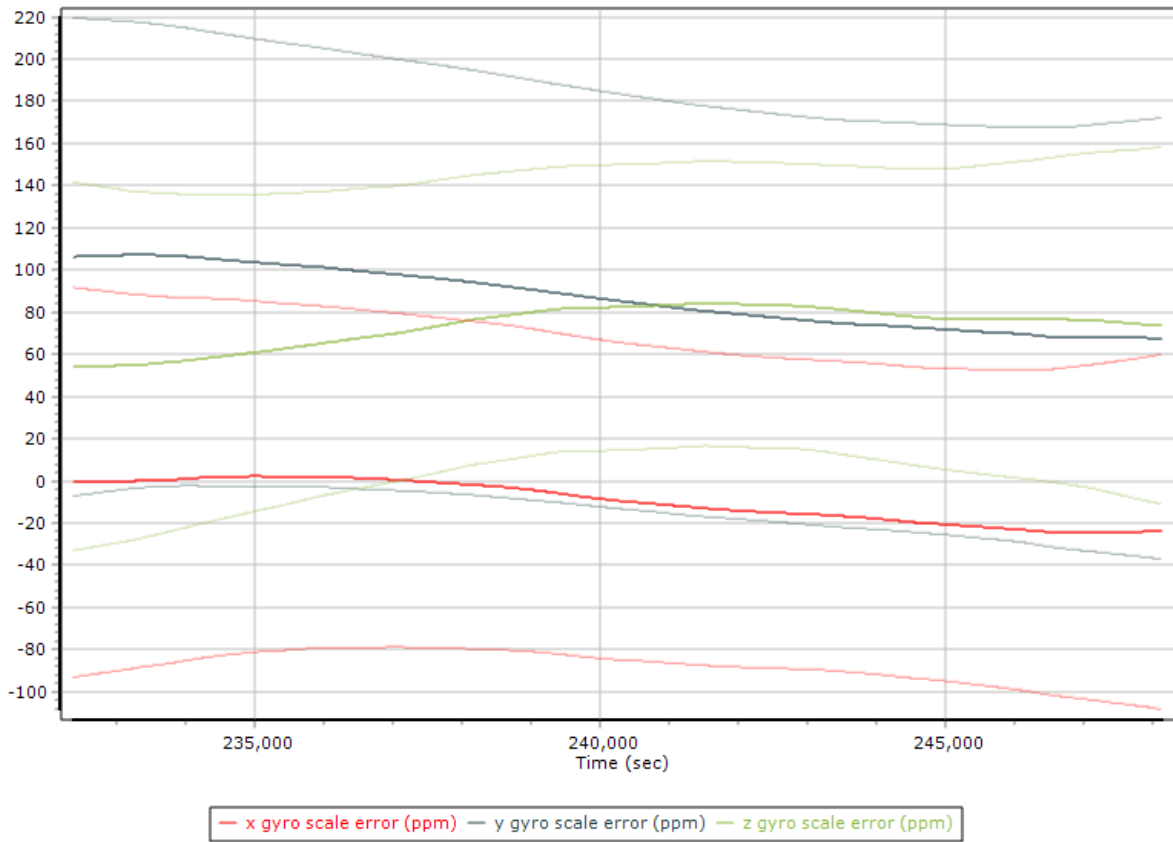












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

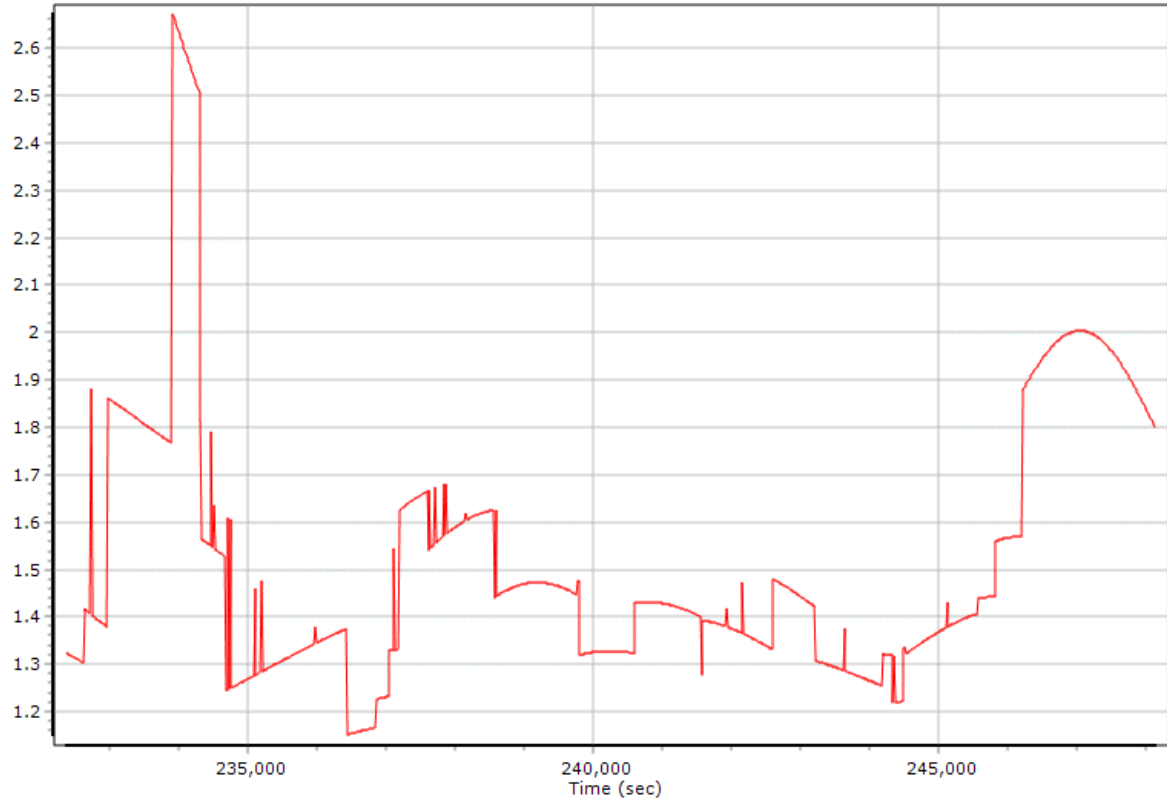
Aircraft to Reference Mounting Angles

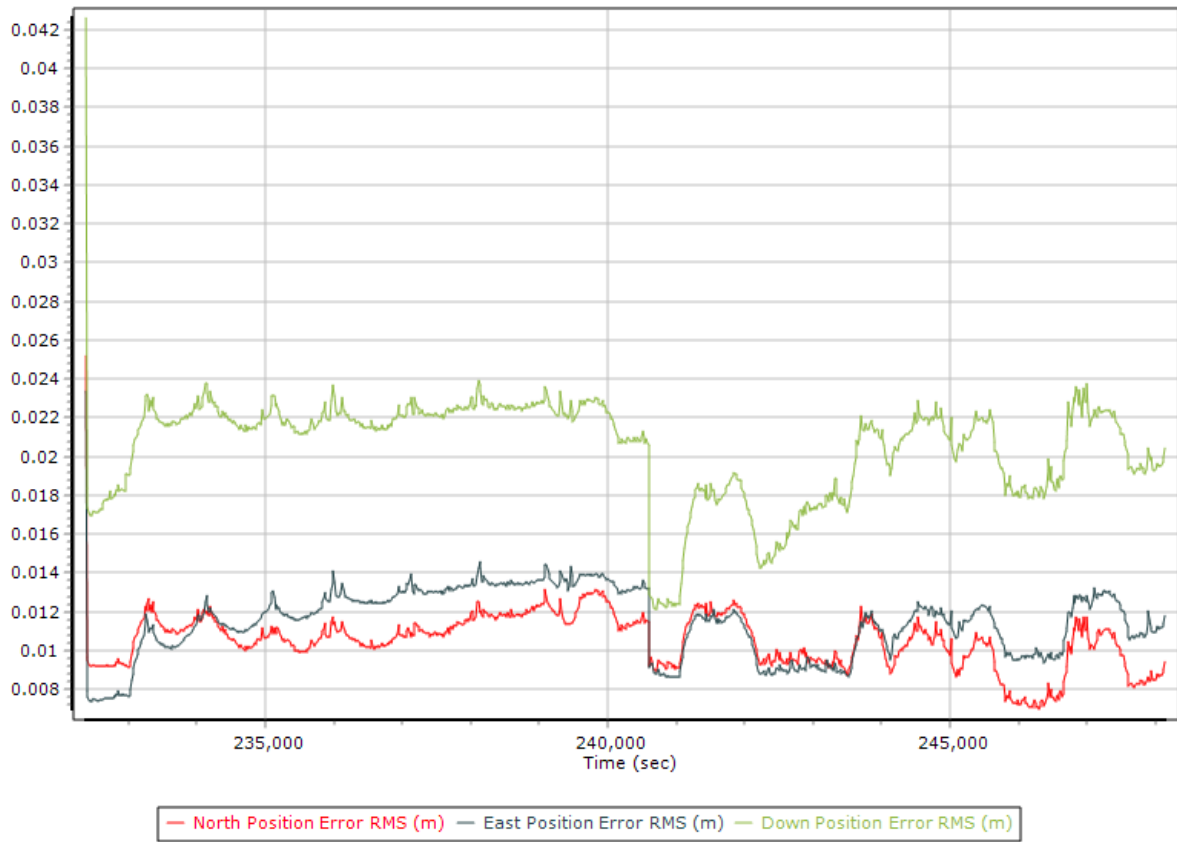
X:

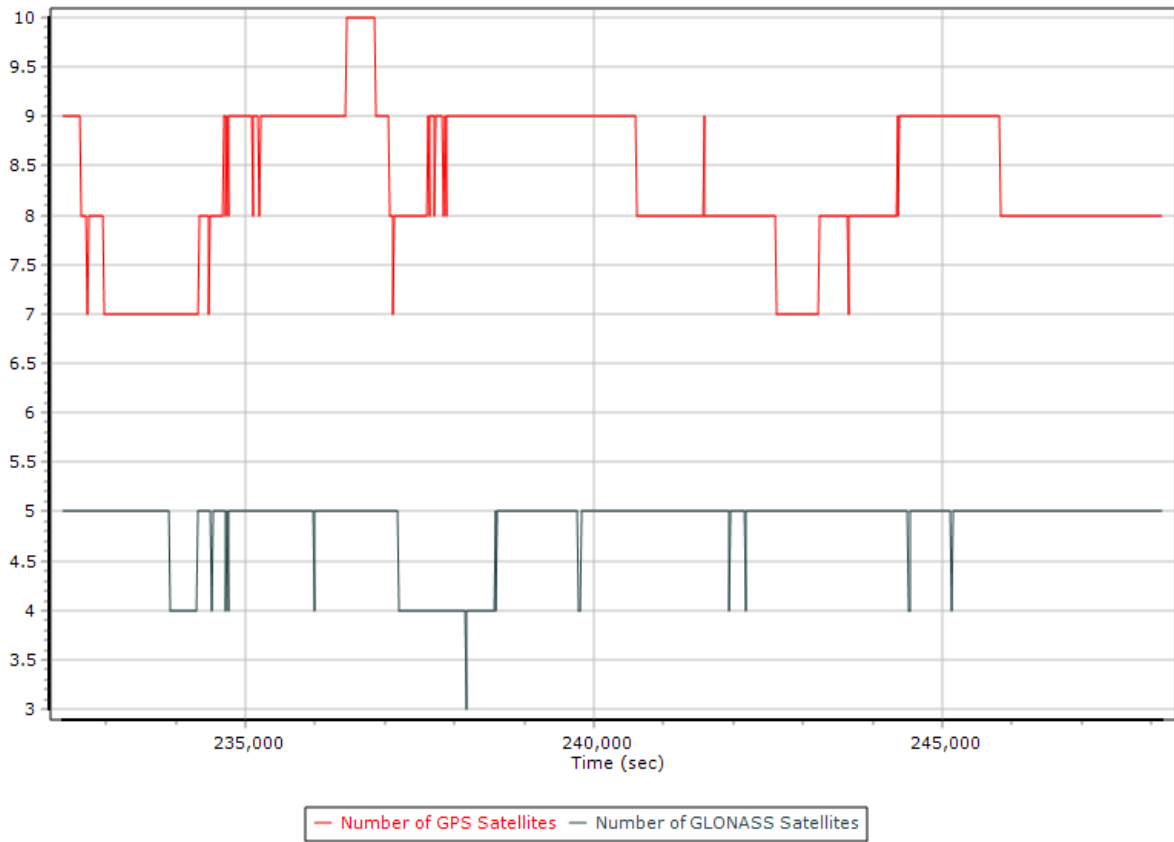
Y:

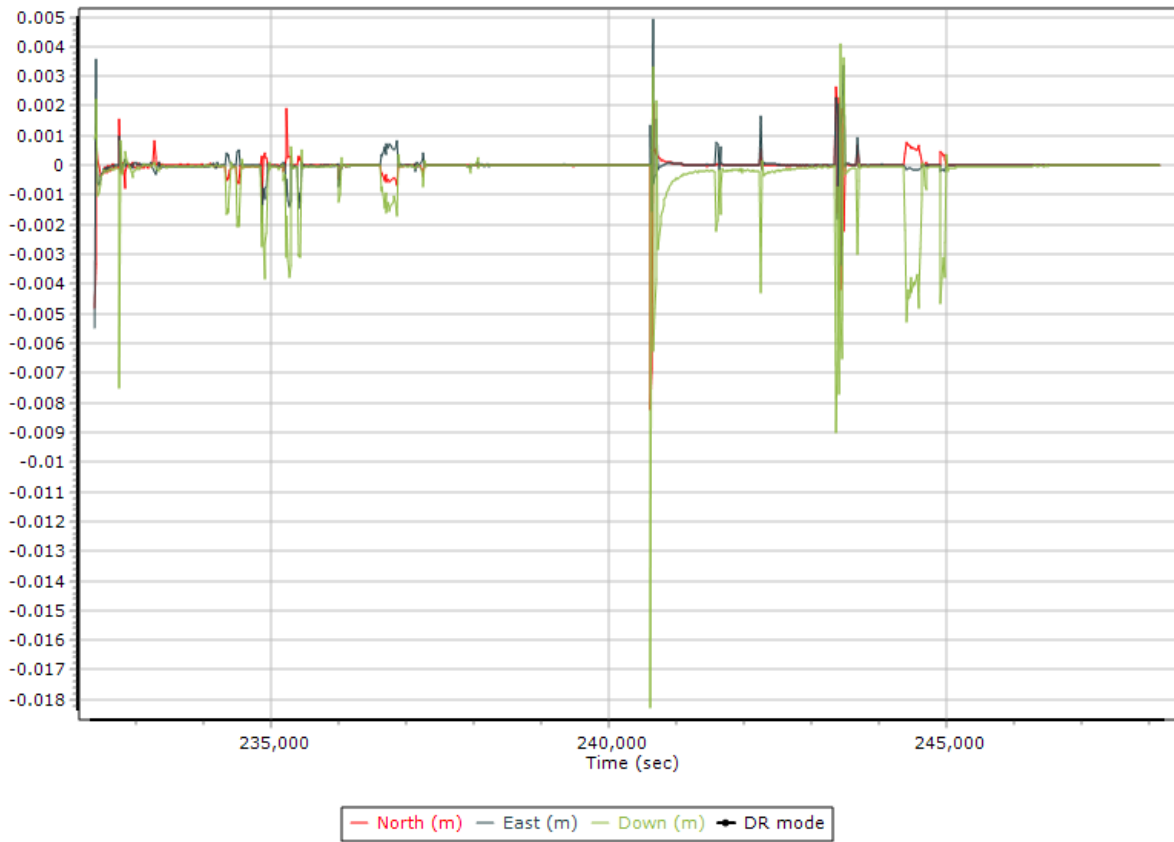
Z:

PDOP









Project Settings [X]

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

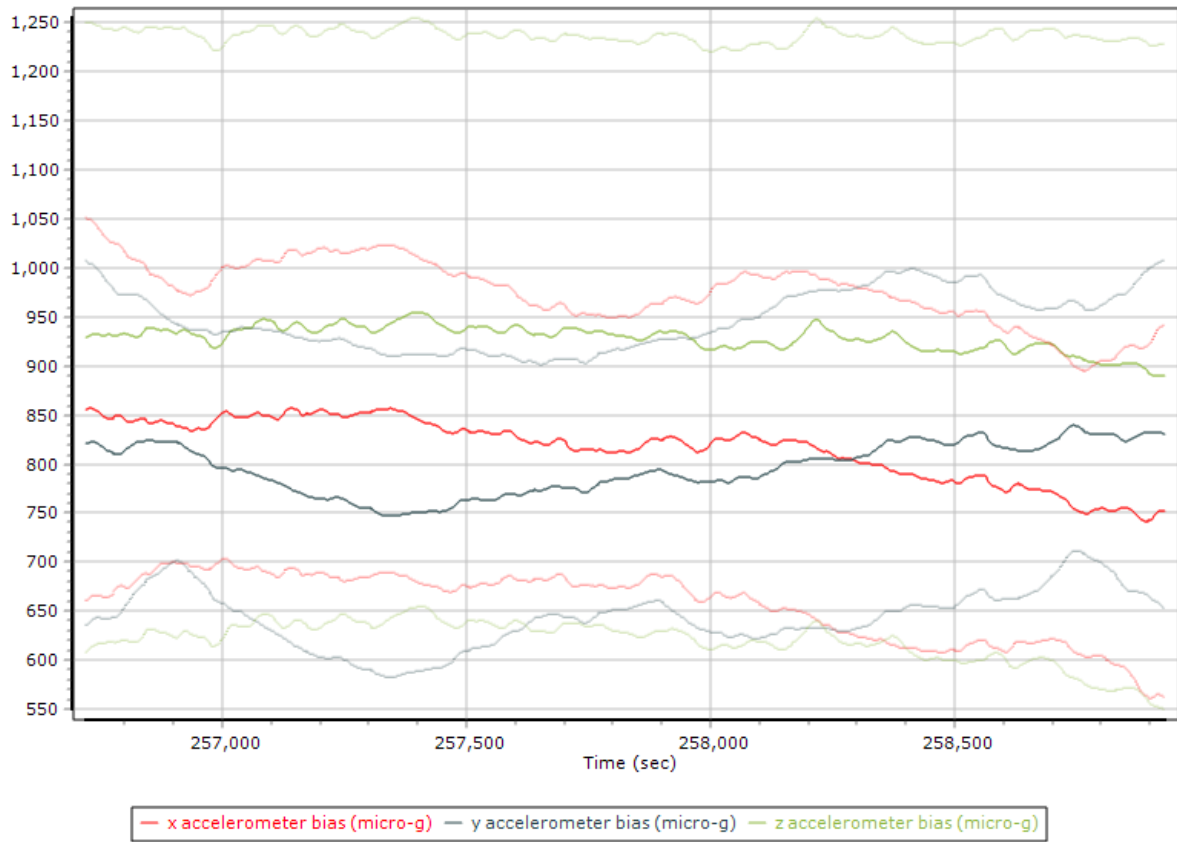
Timing

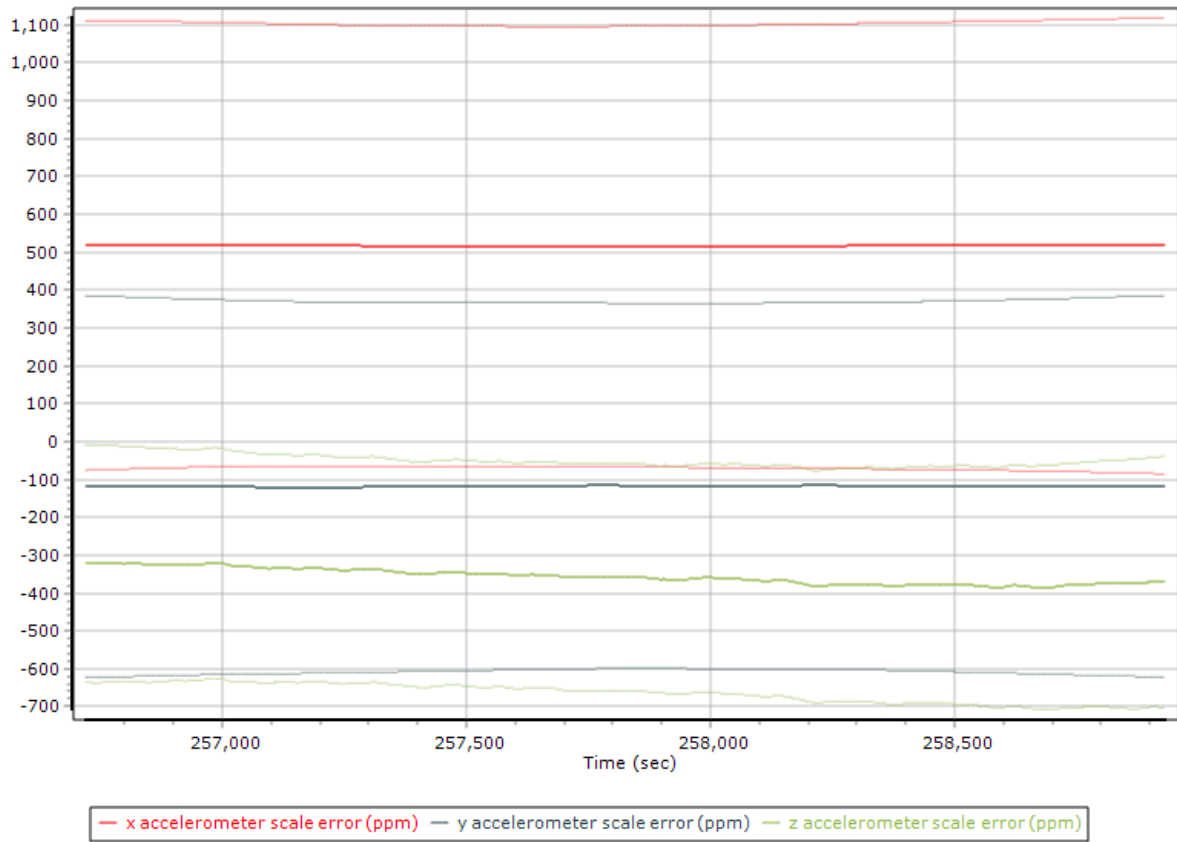
Start: 232387.275
 End: 248157.835
 Entire time interval
 Seconds of start week
 UTC Offset: 18.000

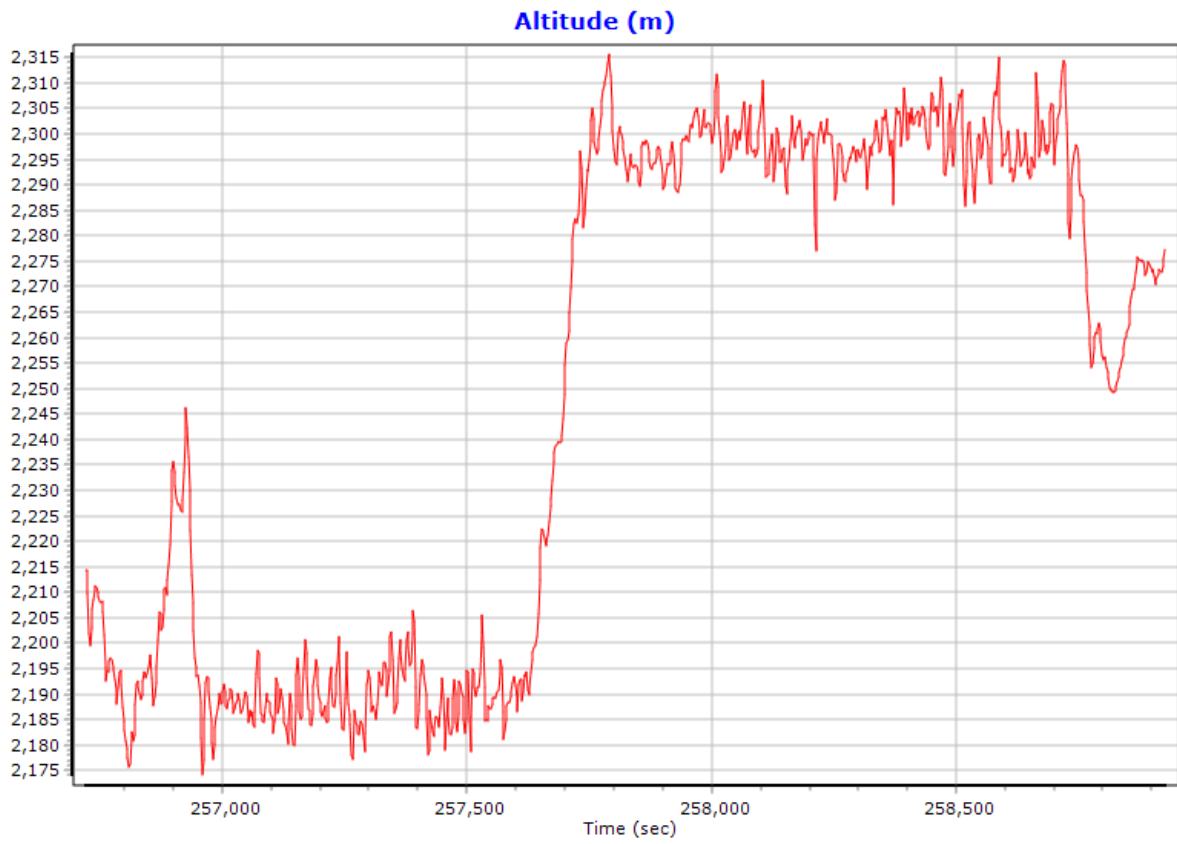
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

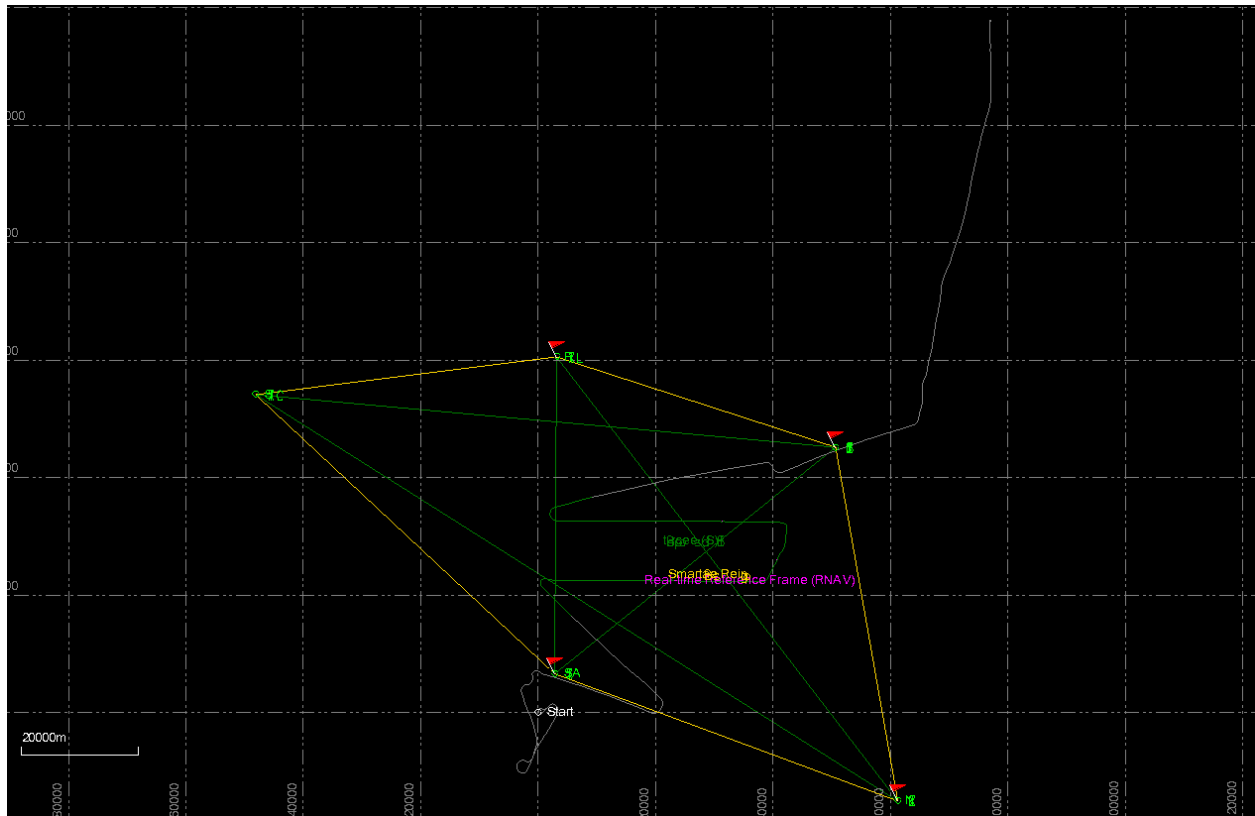
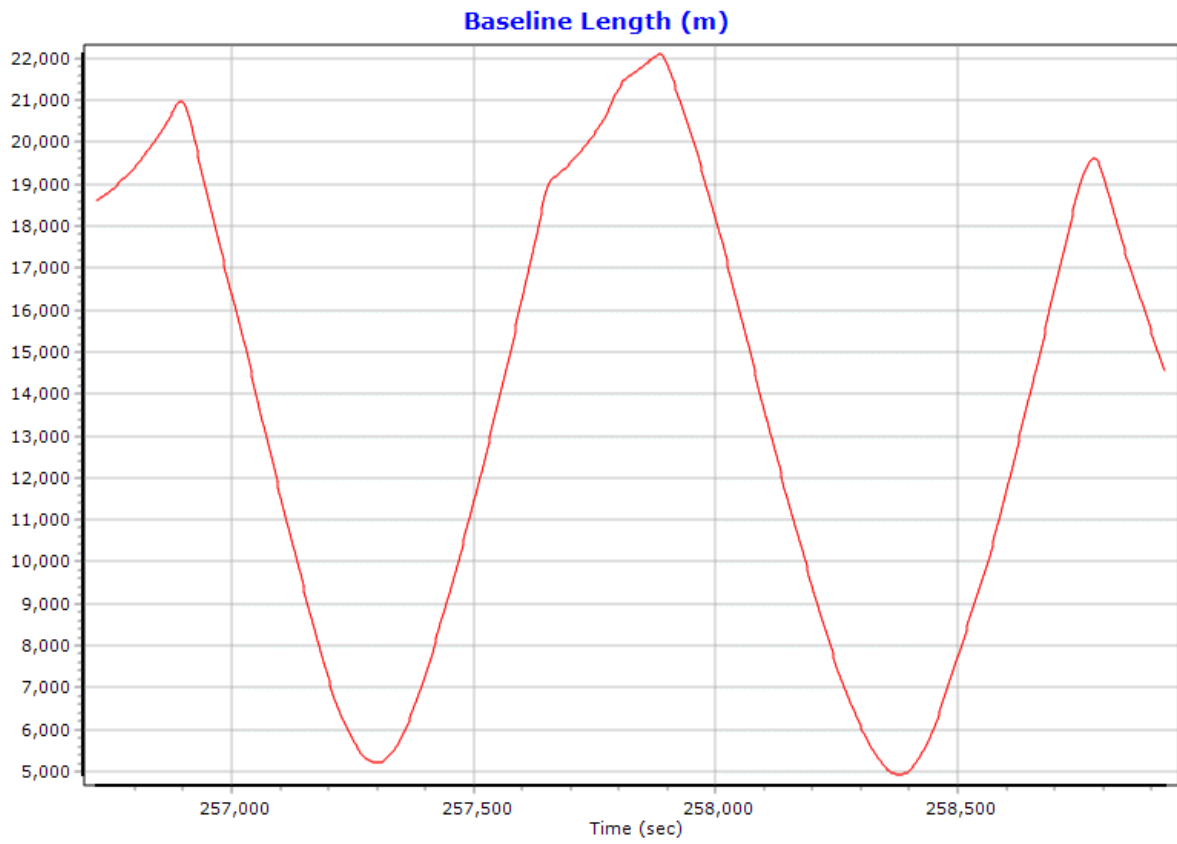
OK Cancel

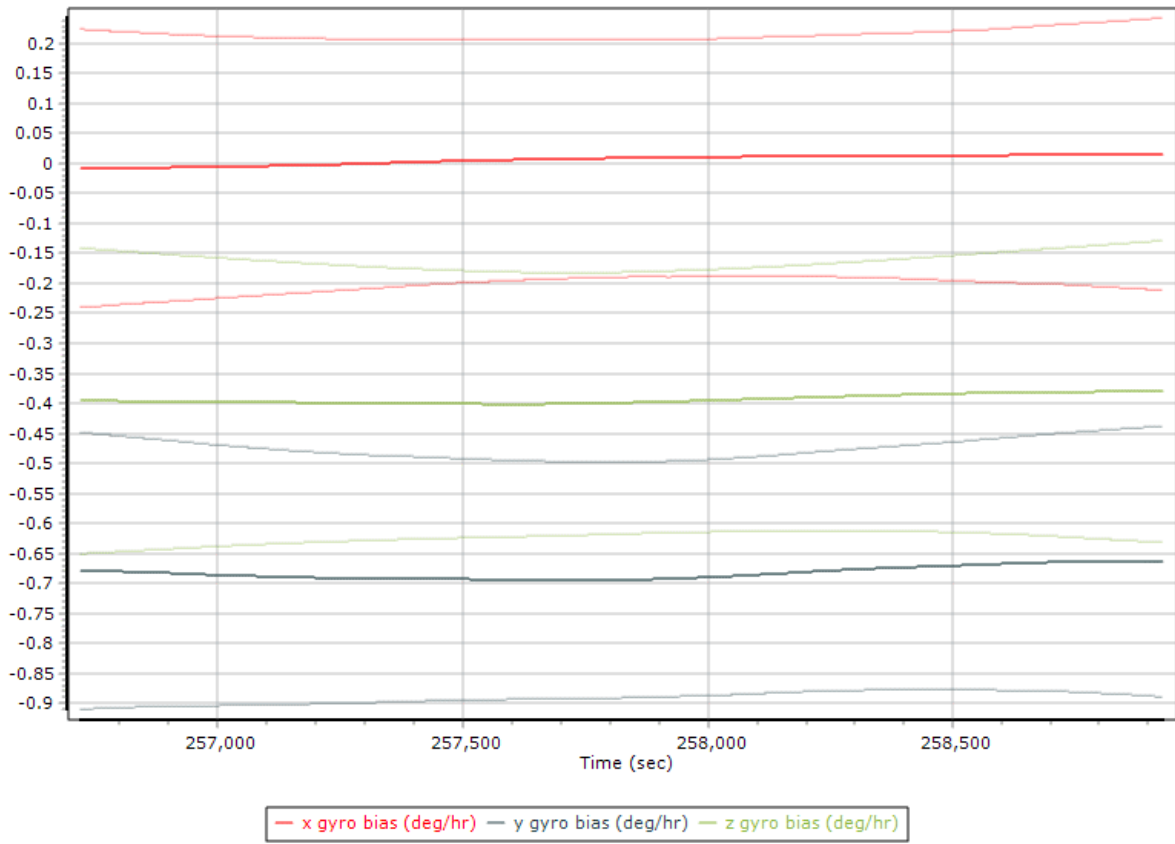
UNB18079B

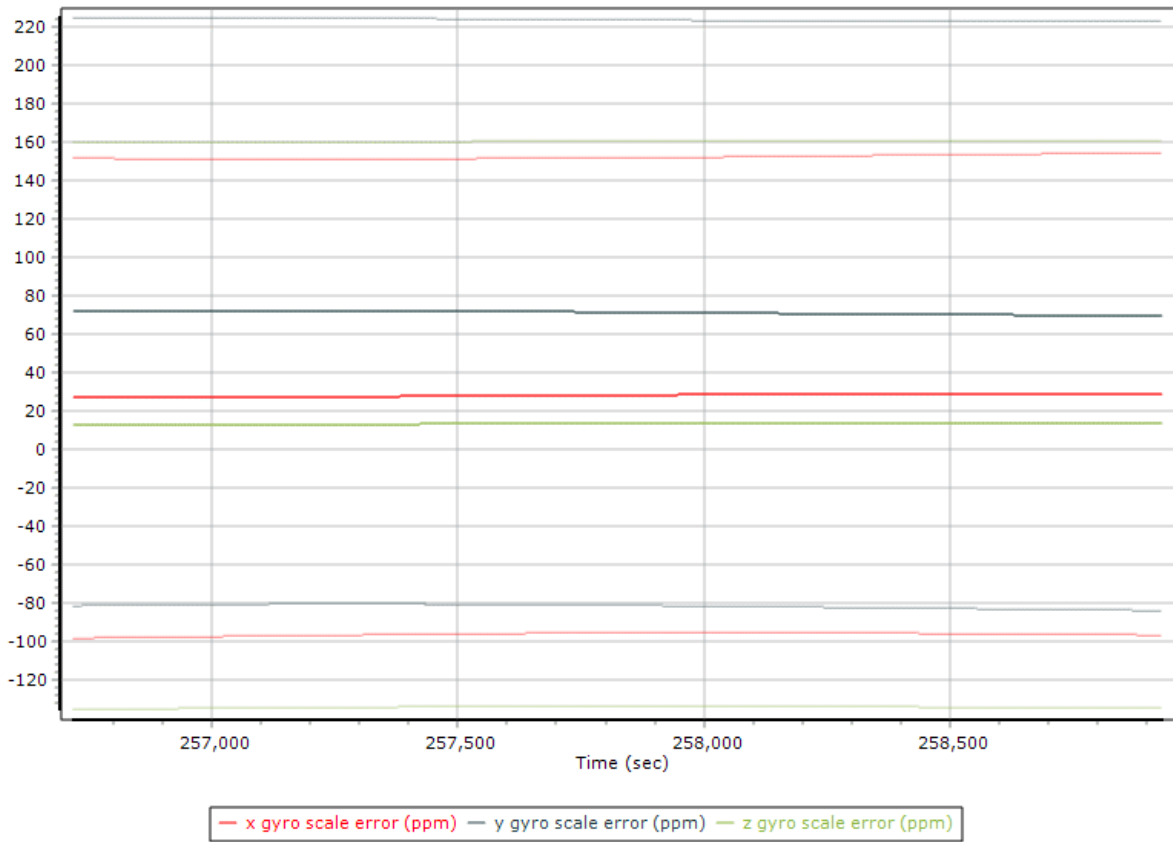












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

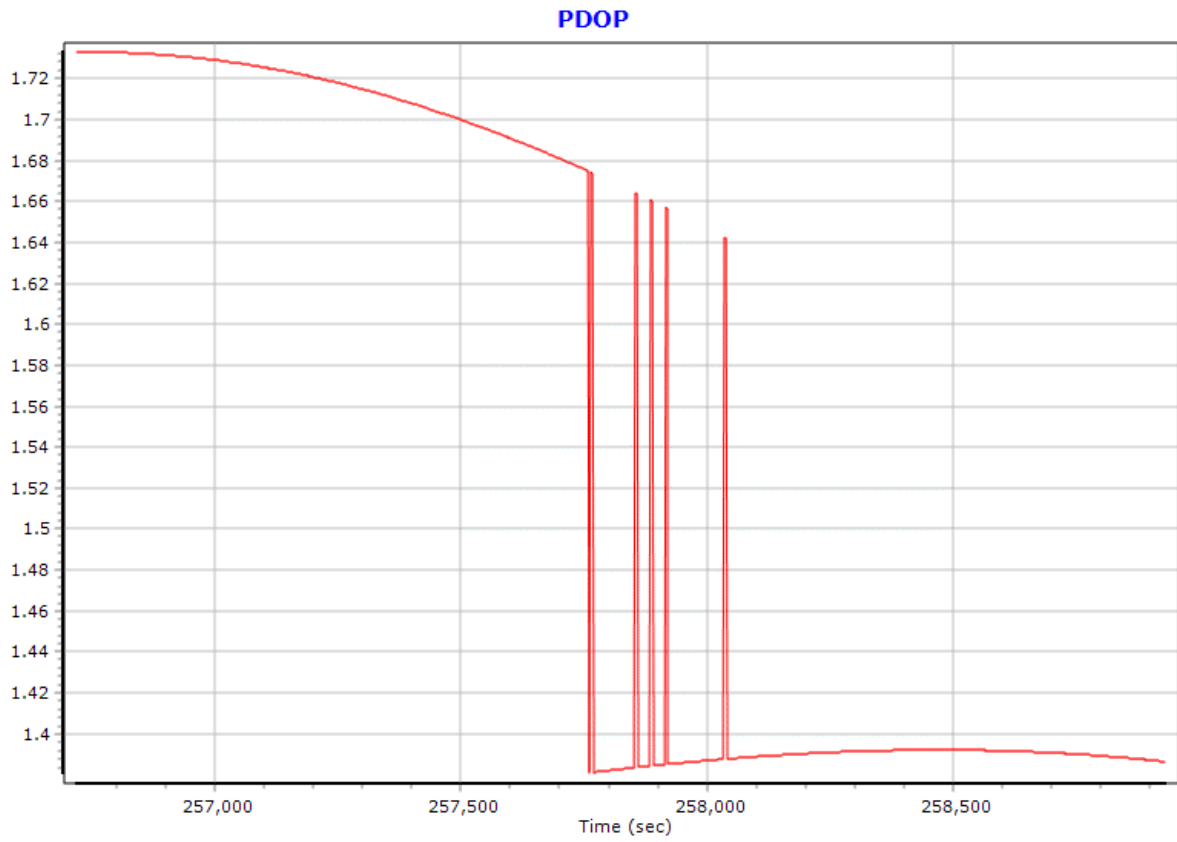
<3cm 10cm 50cm 1m 10m

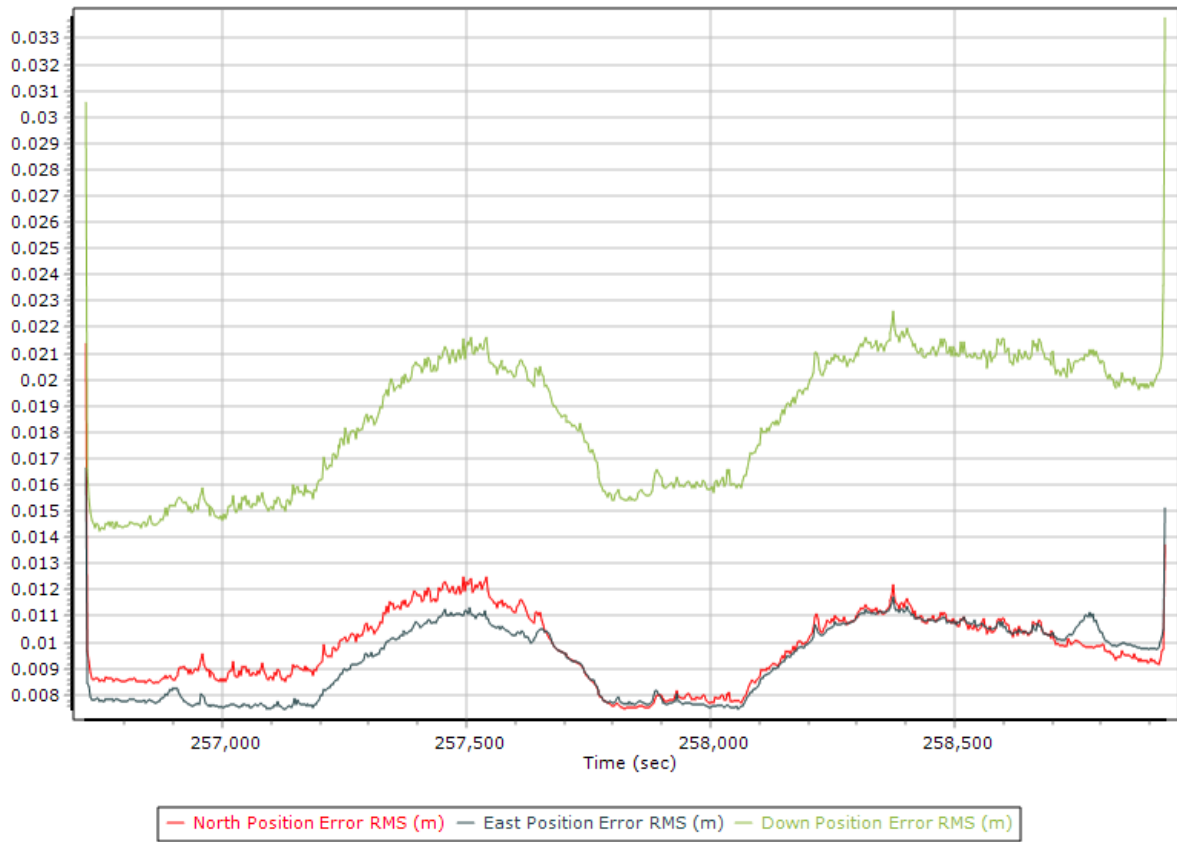
Aircraft to Reference Mounting Angles

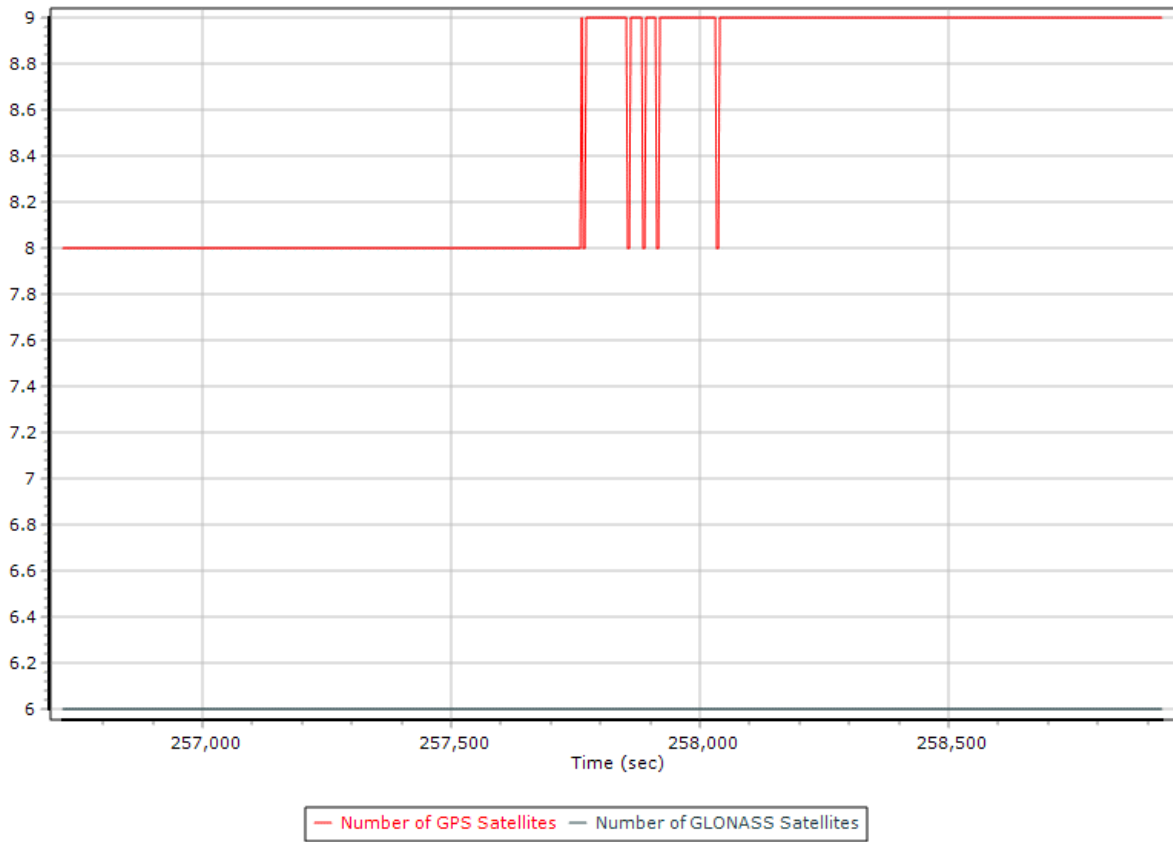
X:

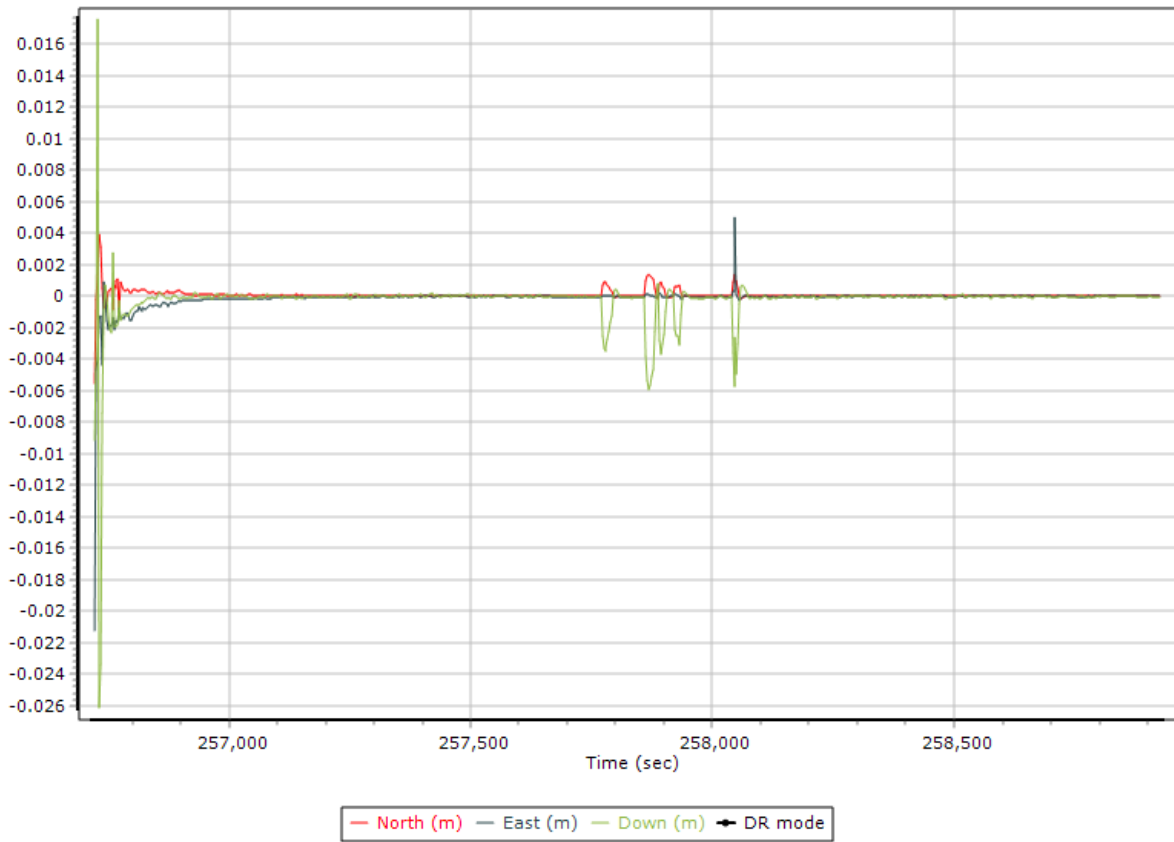
Y:

Z:









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: 256718.689
 End: 258930.770

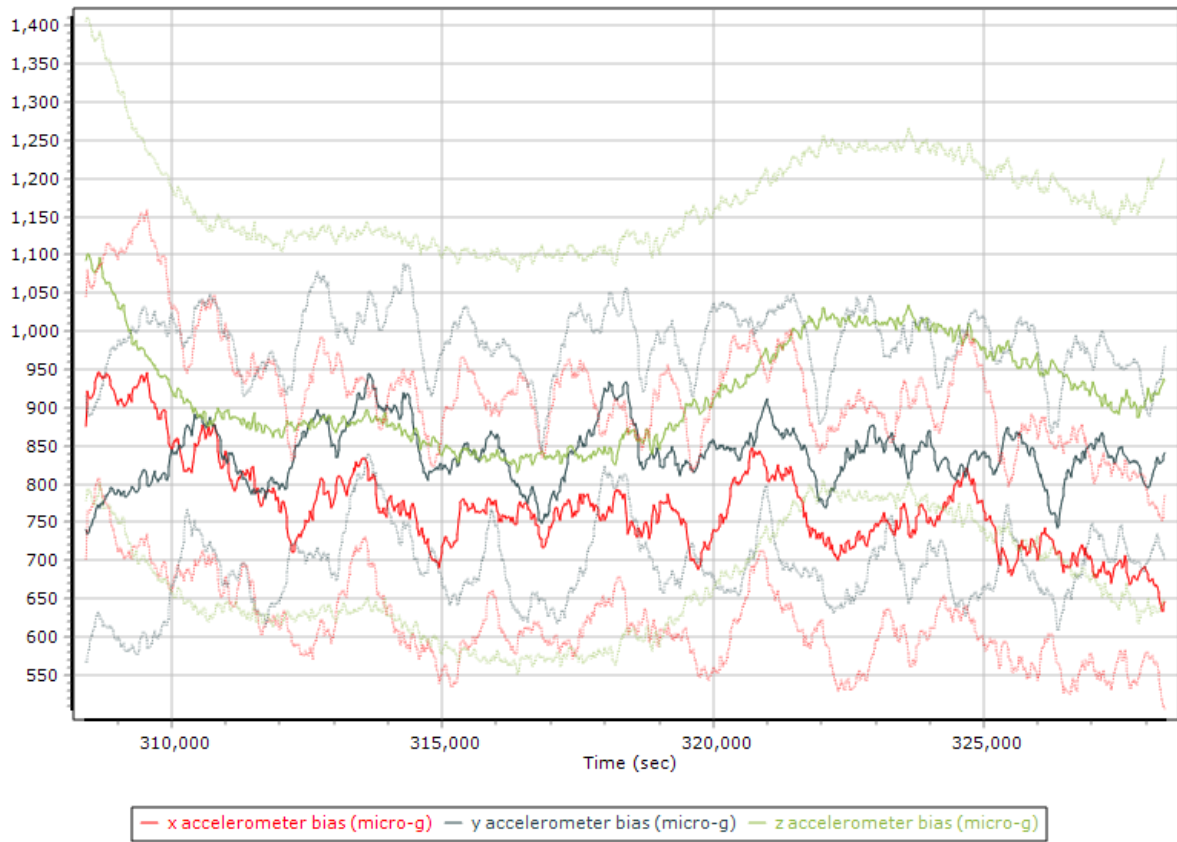
Entire time interval
 Seconds of start week

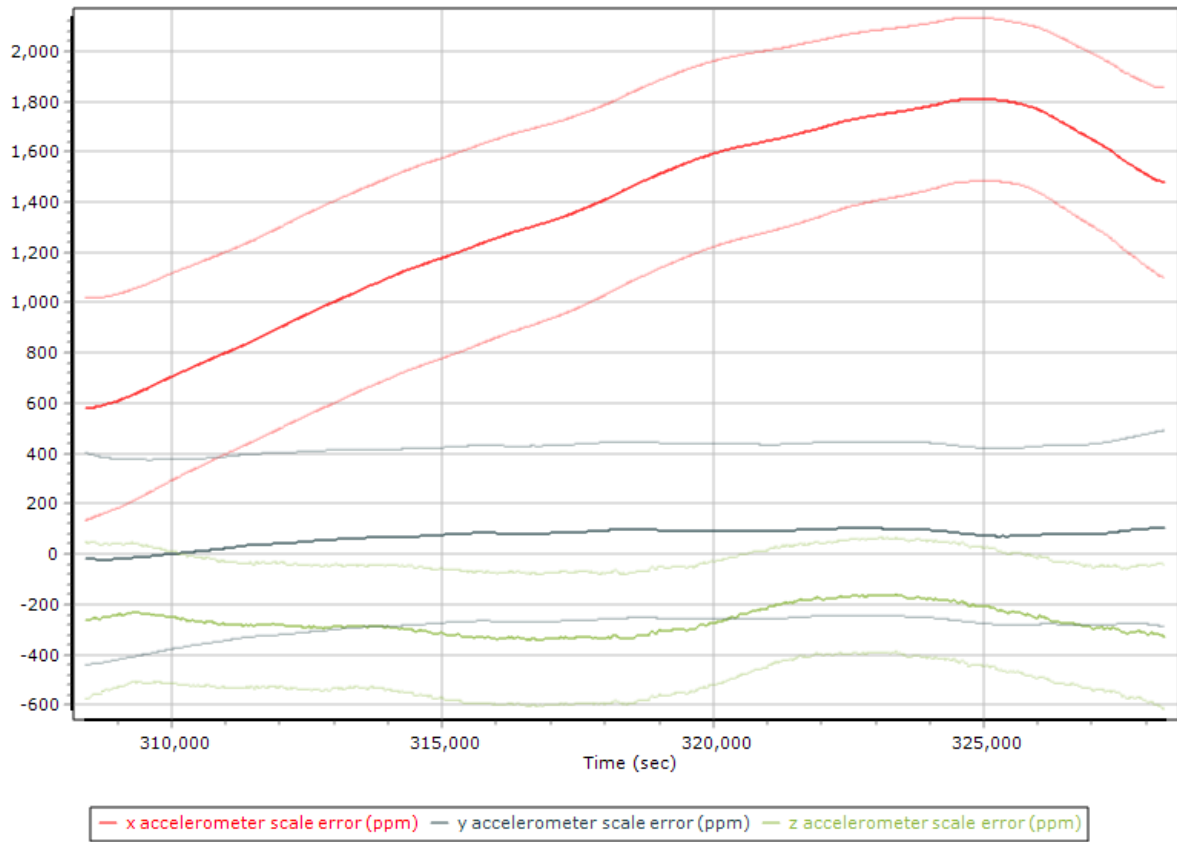
UTC Offset: 18.000

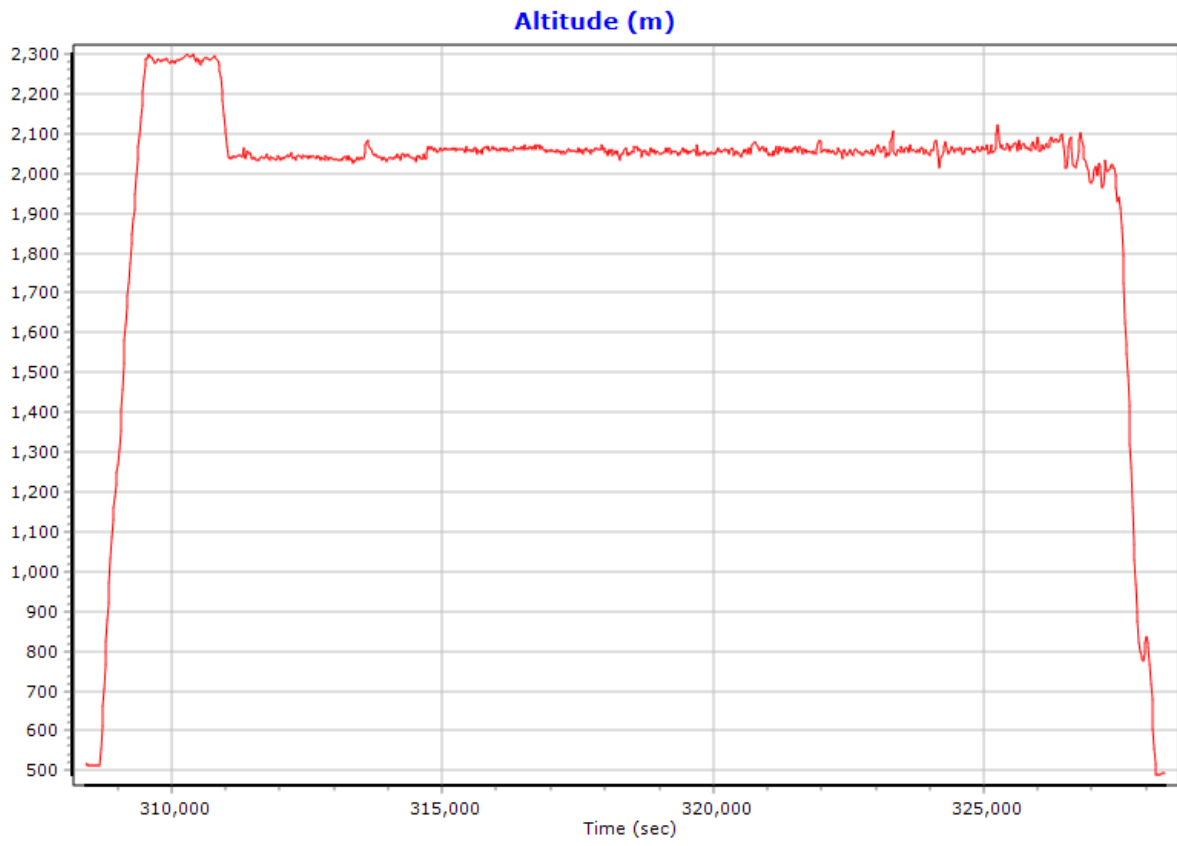
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

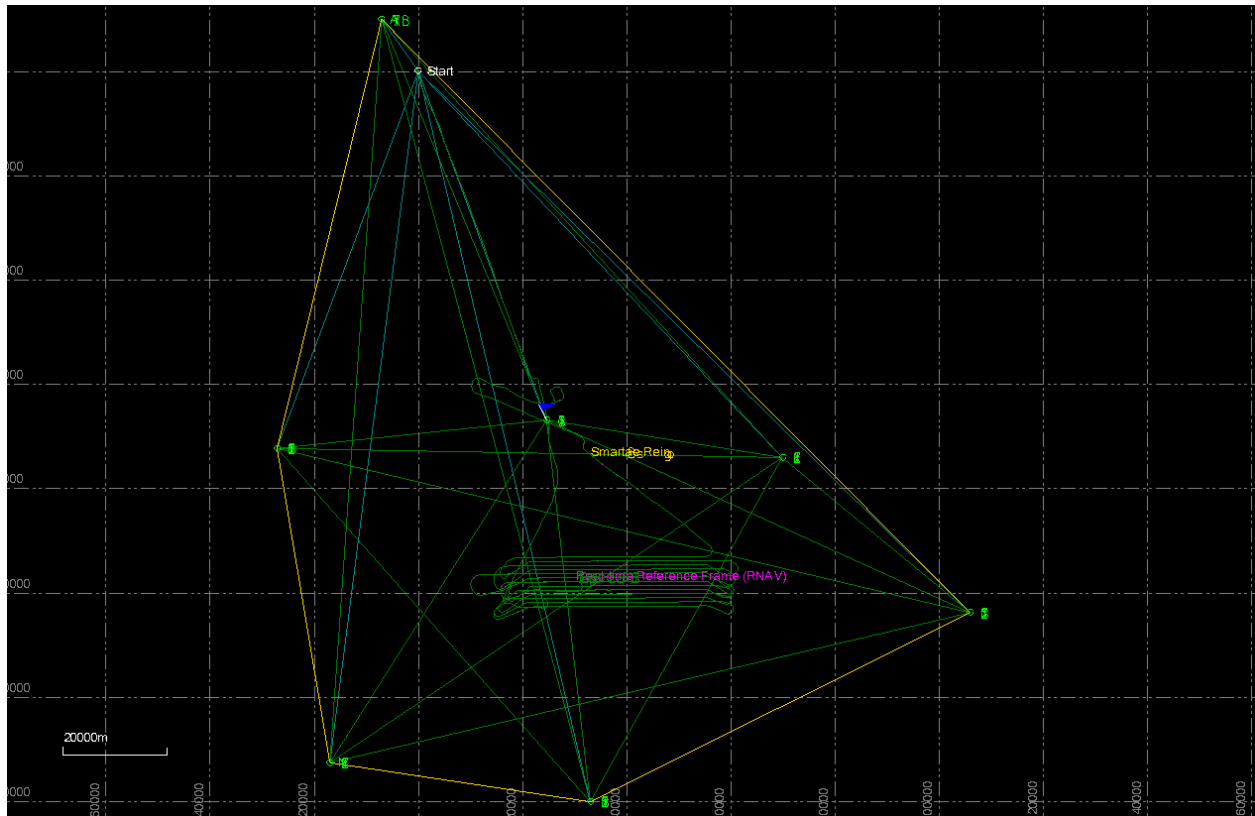
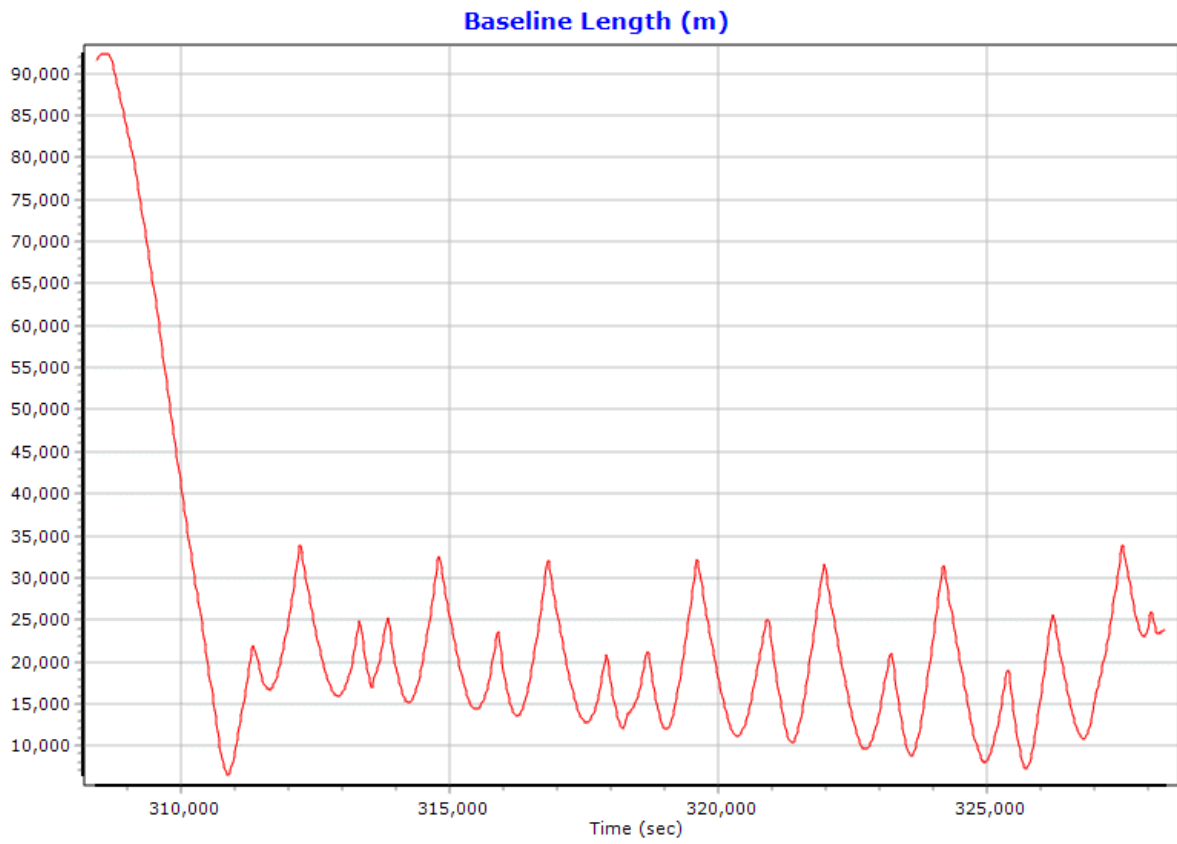
OK Cancel

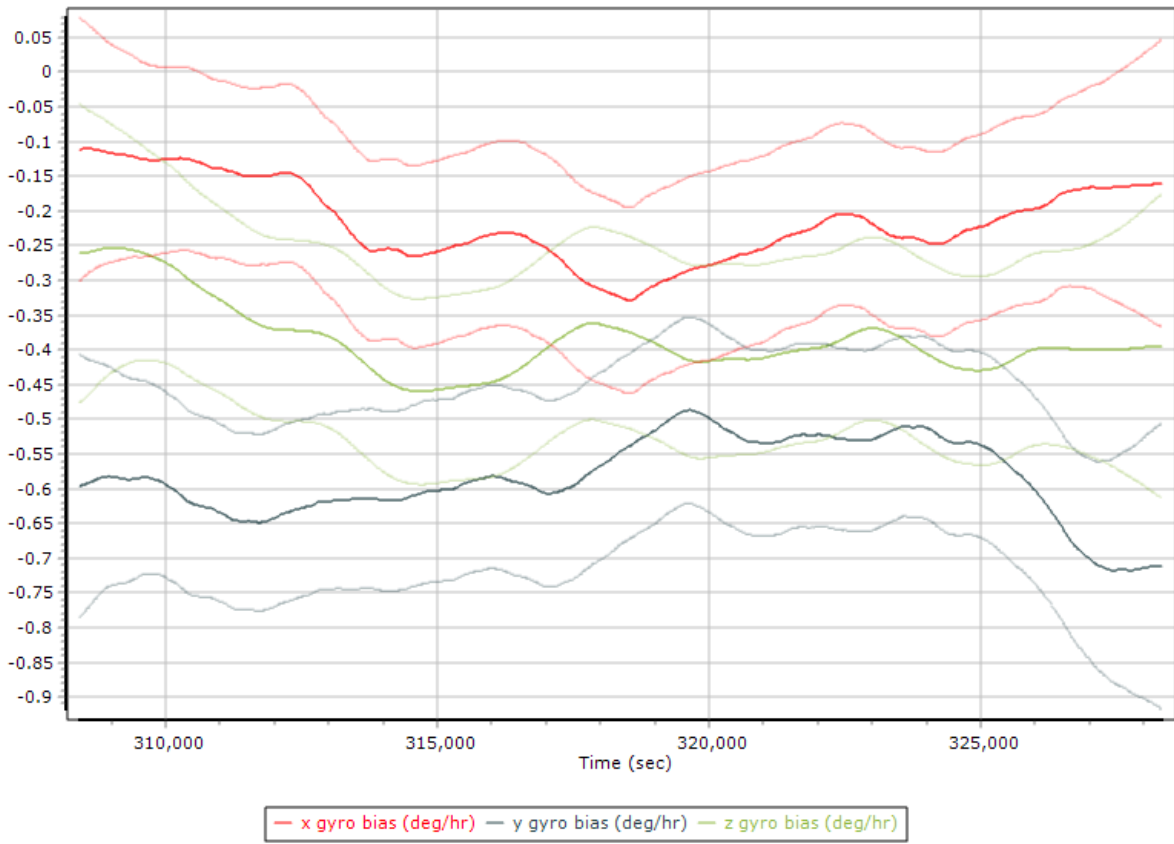
UNB18080A

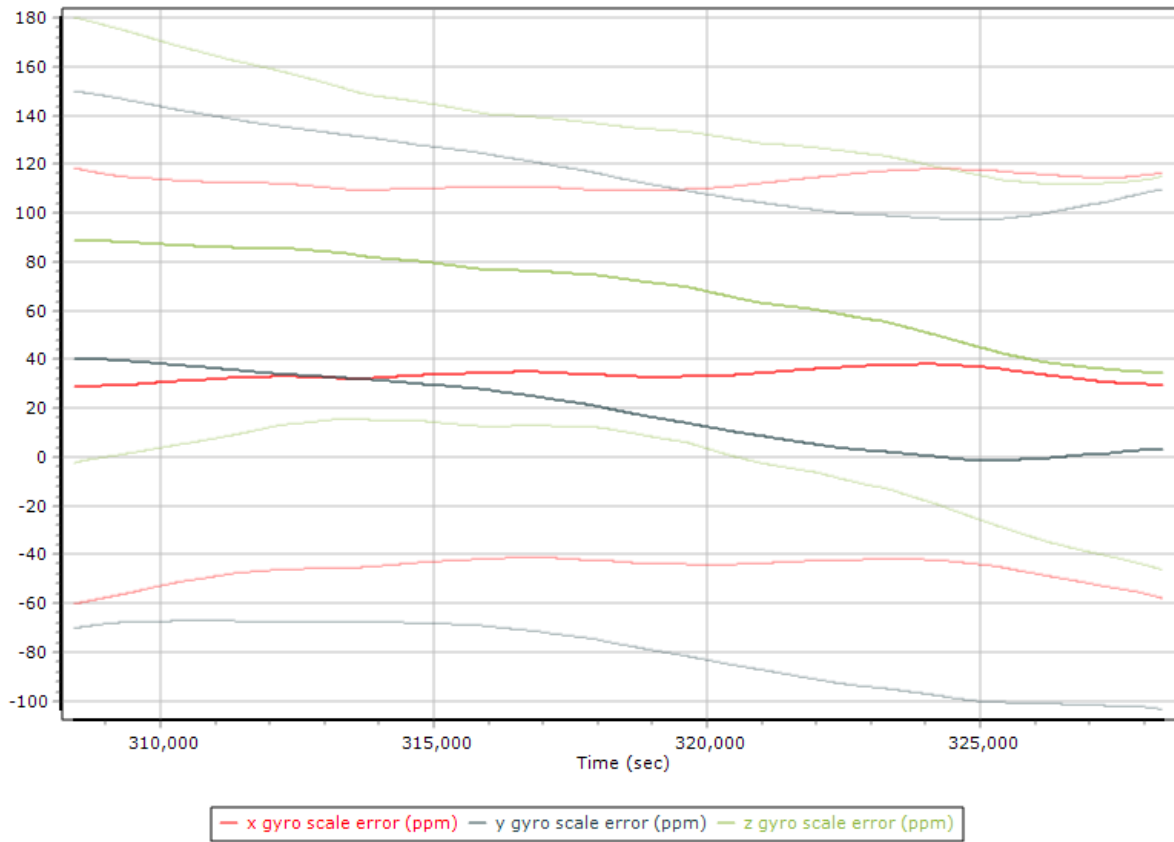












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

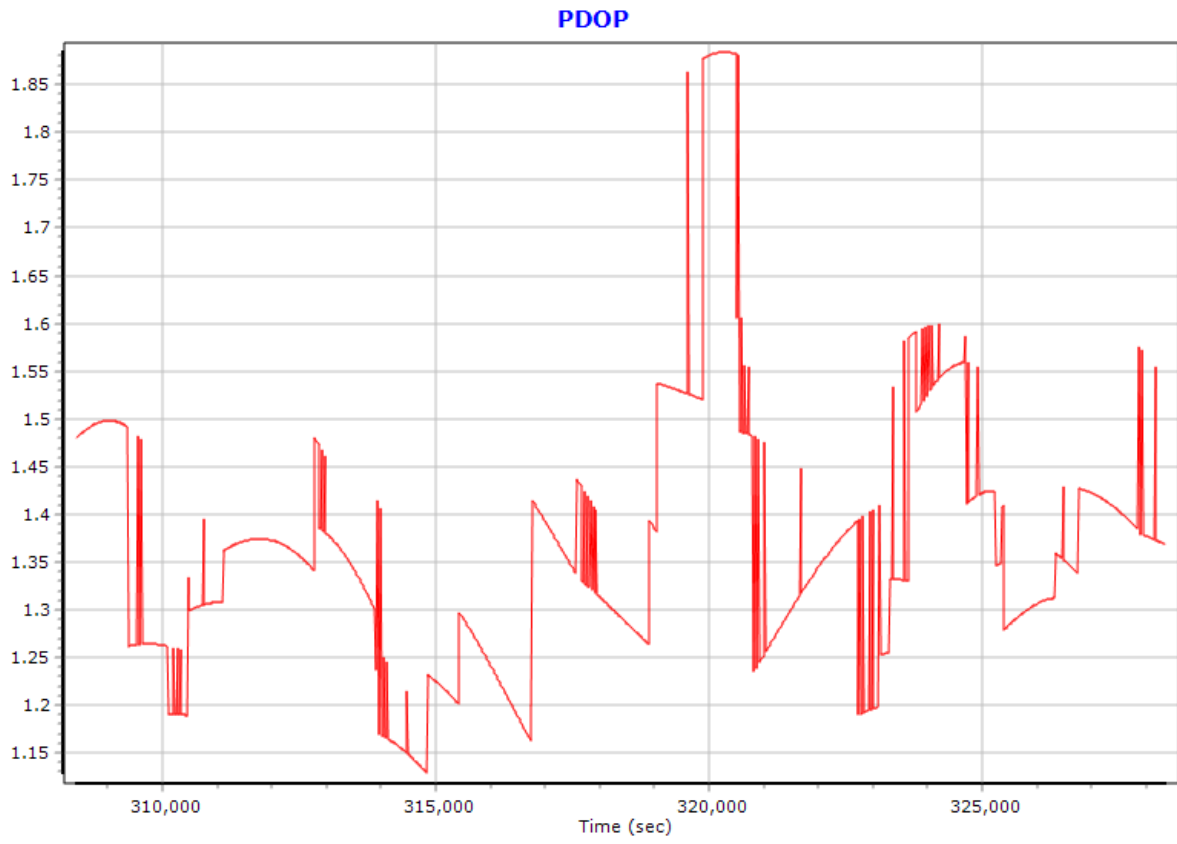
<3cm 10cm 50cm 1m 10m

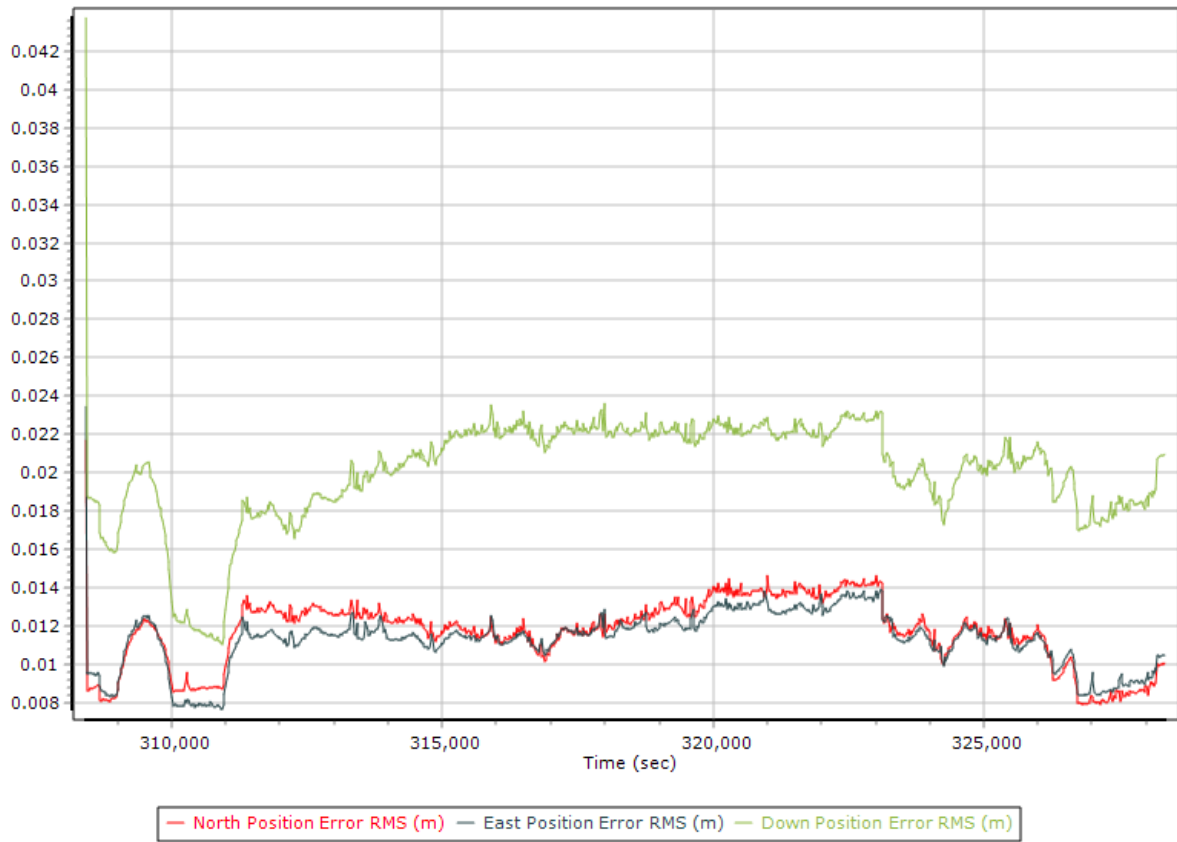
Aircraft to Reference Mounting Angles

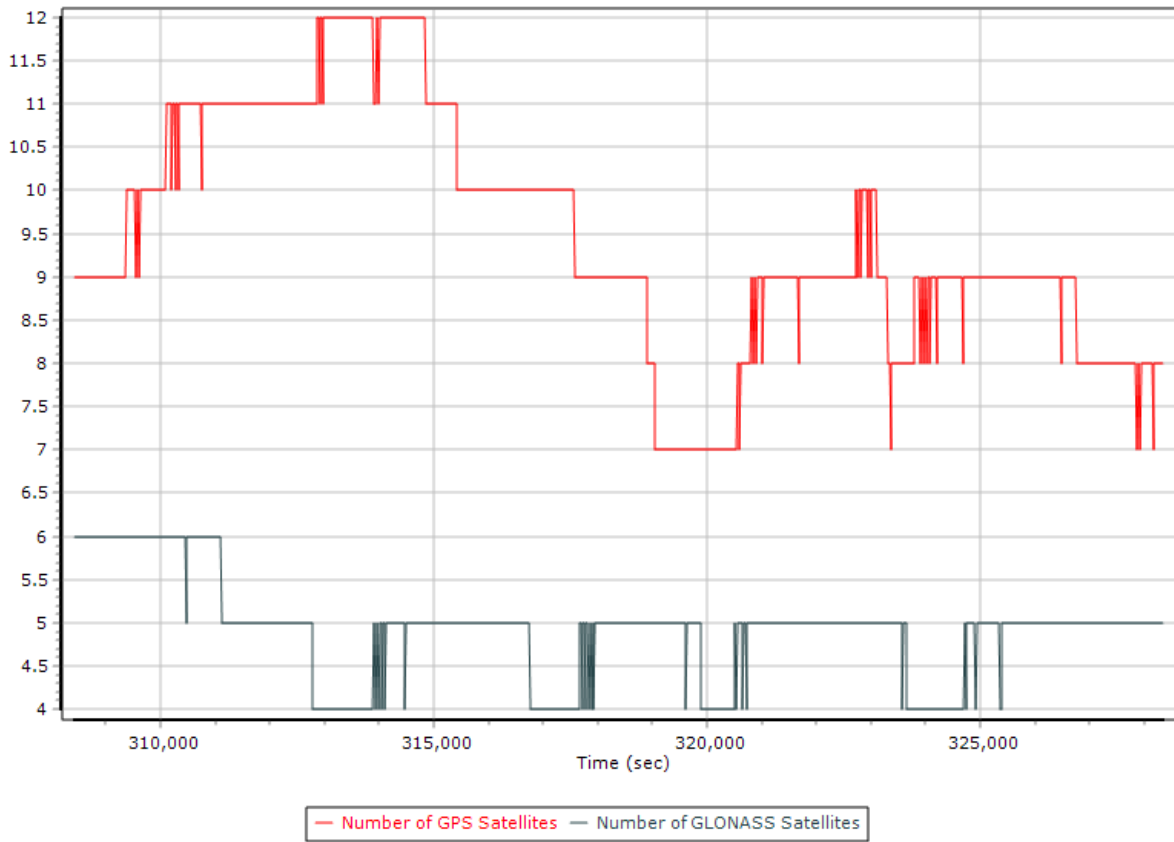
X:

Y:

Z:







Project Settings

- General Information
- Units
- View
- Rover Import
- Satellite Selection**
- GNSS-Inertial Processor
- Export
- Camera
- LIDAR
- SAR

Disable Satellites

GPS | **GLONASS** | BEIDOU | QZSS

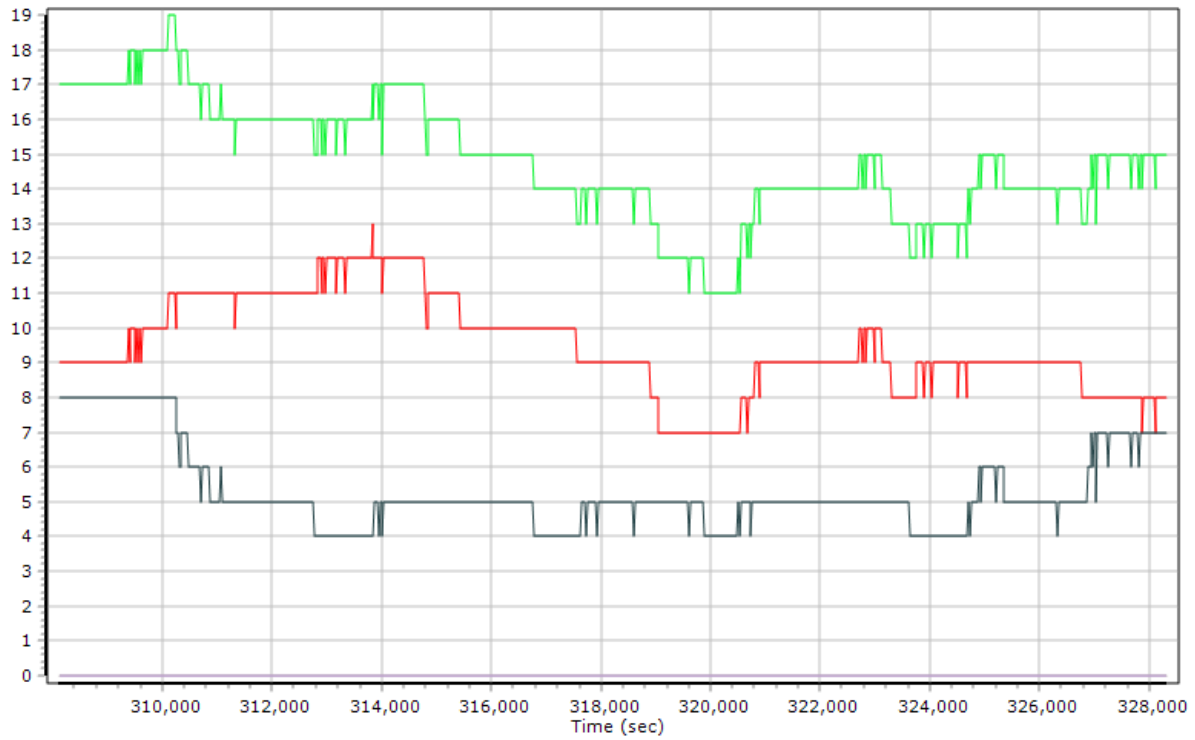
<input type="checkbox"/> PRN 1	<input type="checkbox"/> PRN 10	<input type="checkbox"/> PRN 19	<input type="checkbox"/> PRN 28
<input type="checkbox"/> PRN 2	<input type="checkbox"/> PRN 11	<input type="checkbox"/> PRN 20	<input type="checkbox"/> PRN 29
<input type="checkbox"/> PRN 3	<input type="checkbox"/> PRN 12	<input type="checkbox"/> PRN 21	<input type="checkbox"/> PRN 30
<input type="checkbox"/> PRN 4	<input type="checkbox"/> PRN 13	<input type="checkbox"/> PRN 22	<input type="checkbox"/> PRN 31
<input type="checkbox"/> PRN 5	<input type="checkbox"/> PRN 14	<input type="checkbox"/> PRN 23	<input type="checkbox"/> PRN 32
<input type="checkbox"/> PRN 6	<input type="checkbox"/> PRN 15	<input type="checkbox"/> PRN 24	
<input type="checkbox"/> PRN 7	<input type="checkbox"/> PRN 16	<input type="checkbox"/> PRN 25	
<input type="checkbox"/> PRN 8	<input type="checkbox"/> PRN 17	<input type="checkbox"/> PRN 26	
<input type="checkbox"/> PRN 9	<input type="checkbox"/> PRN 18	<input type="checkbox"/> PRN 27	

Elevation Mask Angle:

Force GPS Only

OK Cancel

Number of SVs in solution



— Number of GPS — Number of GLONASS — Number of QZSS — Number of BEIDOU — Total Number

Project Settings [X]

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

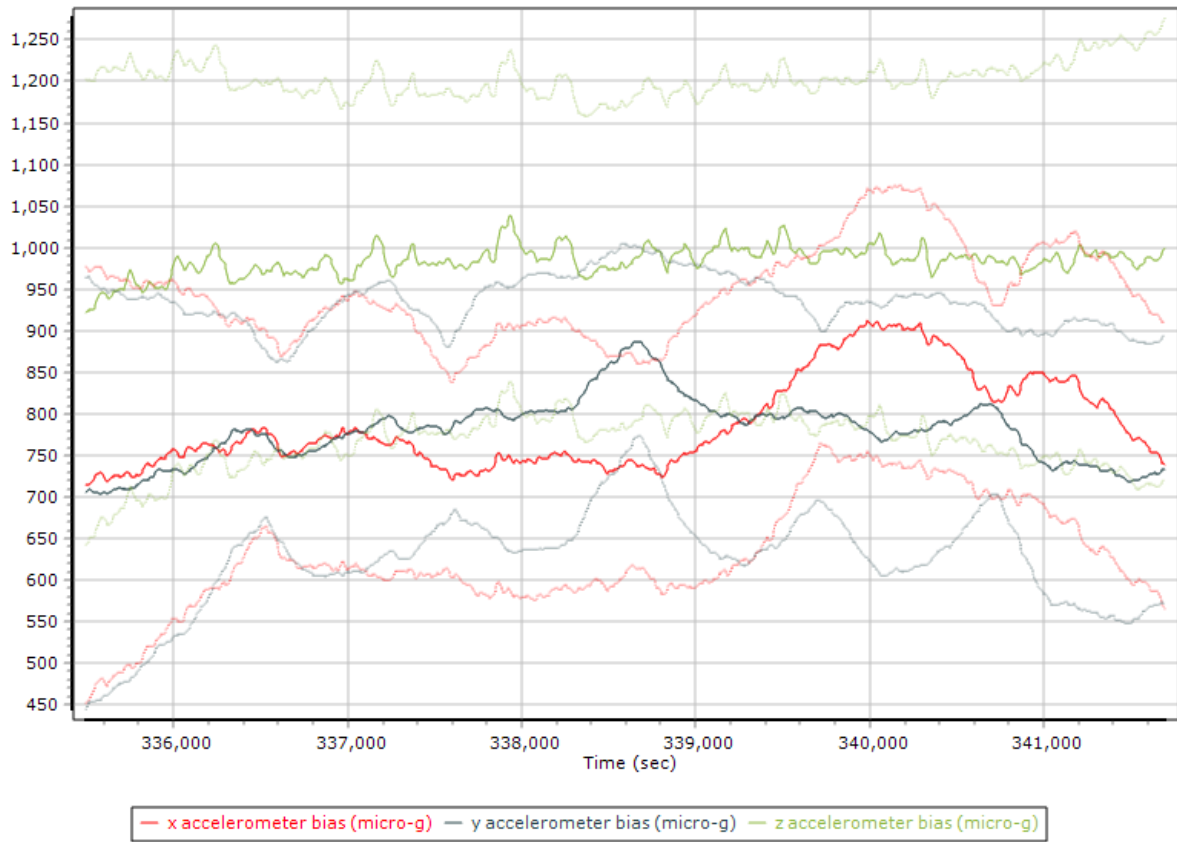
Timing

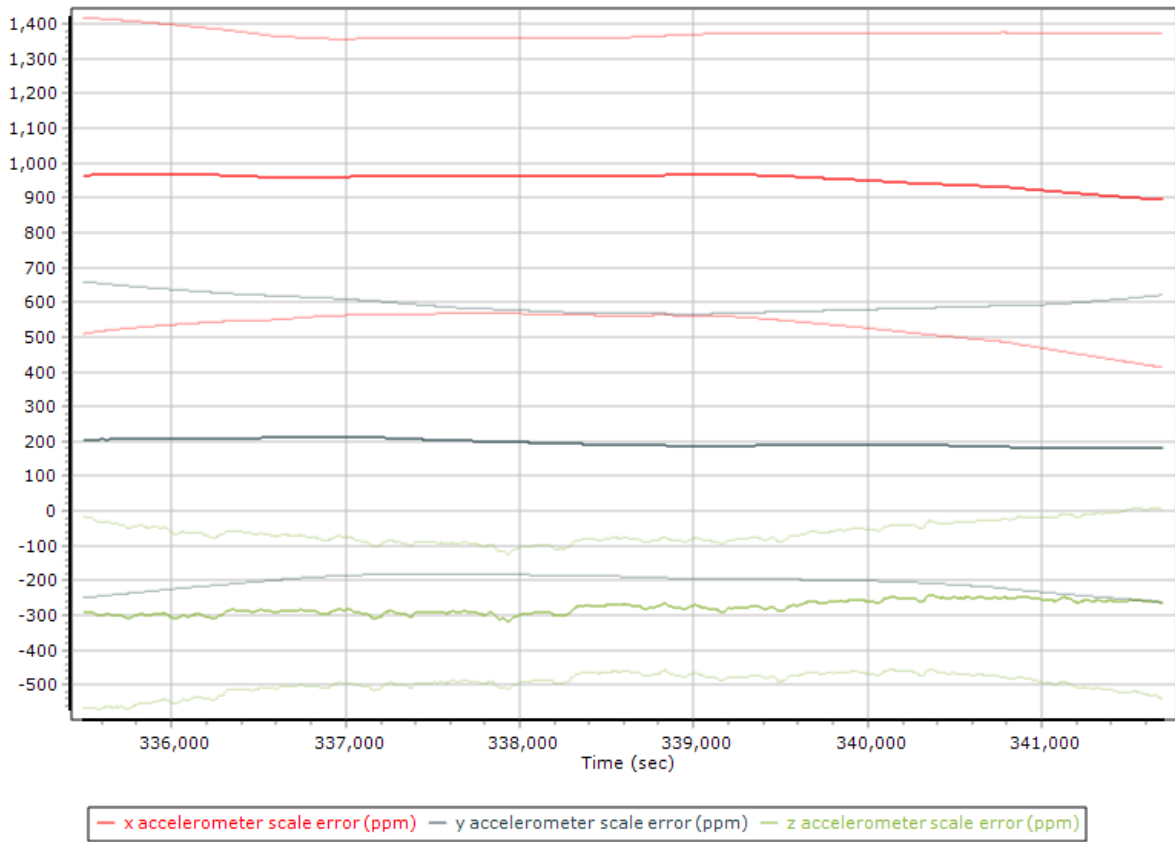
Start: 308096.018
 End: 328363.000
 Entire time interval
 Seconds of start week
 UTC Offset: 18.000

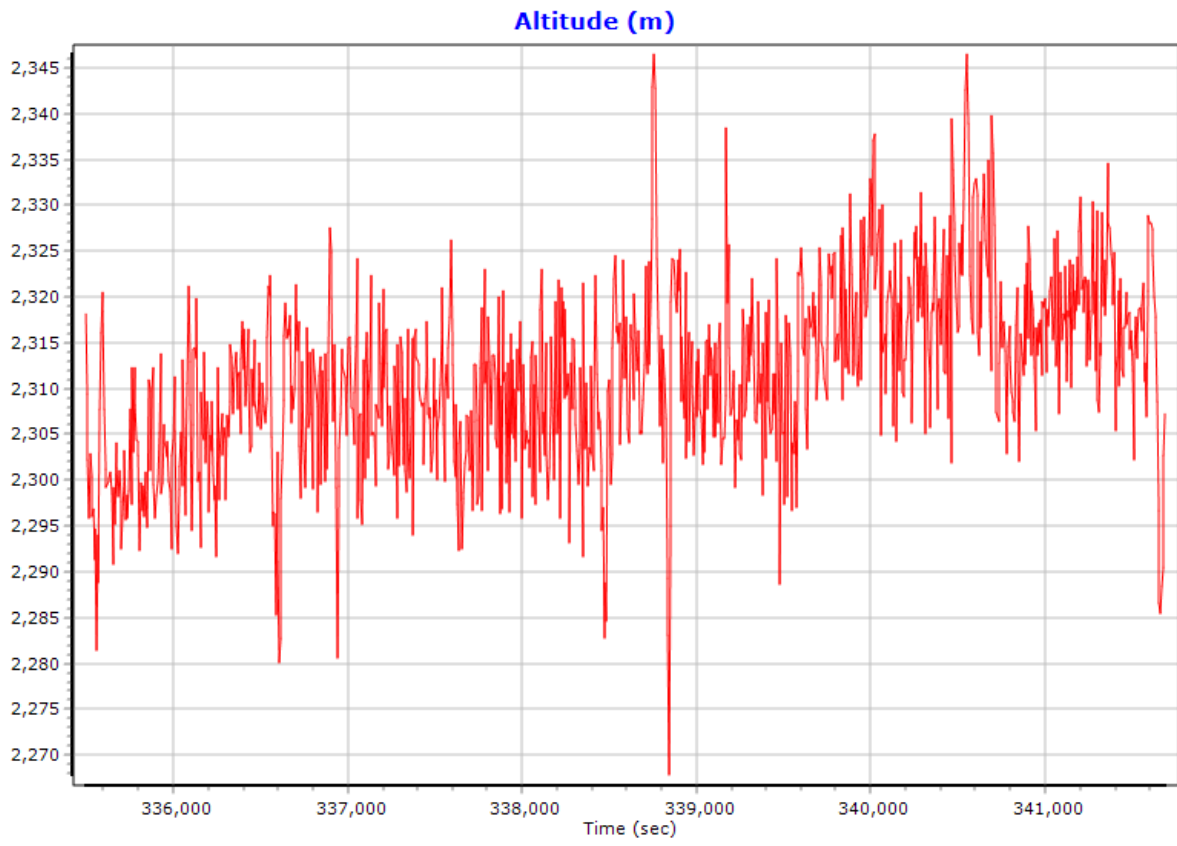
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

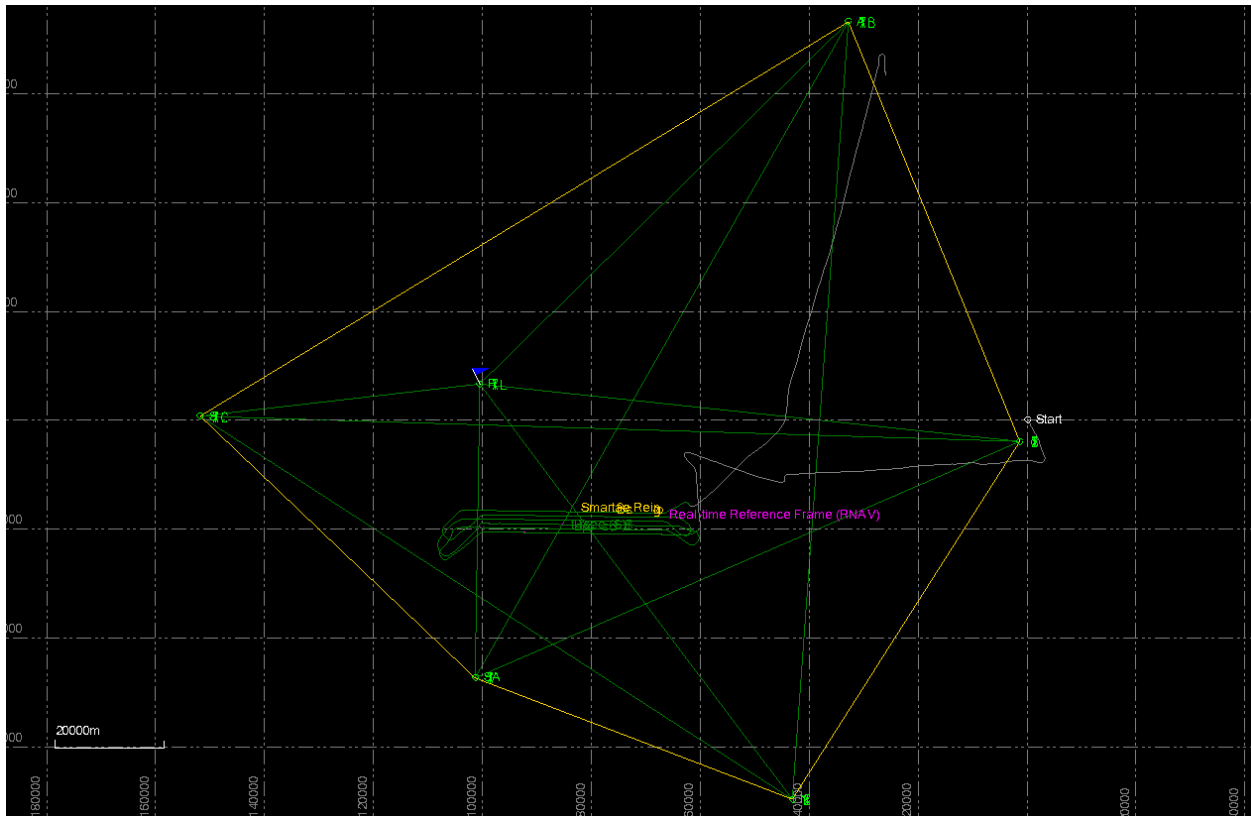
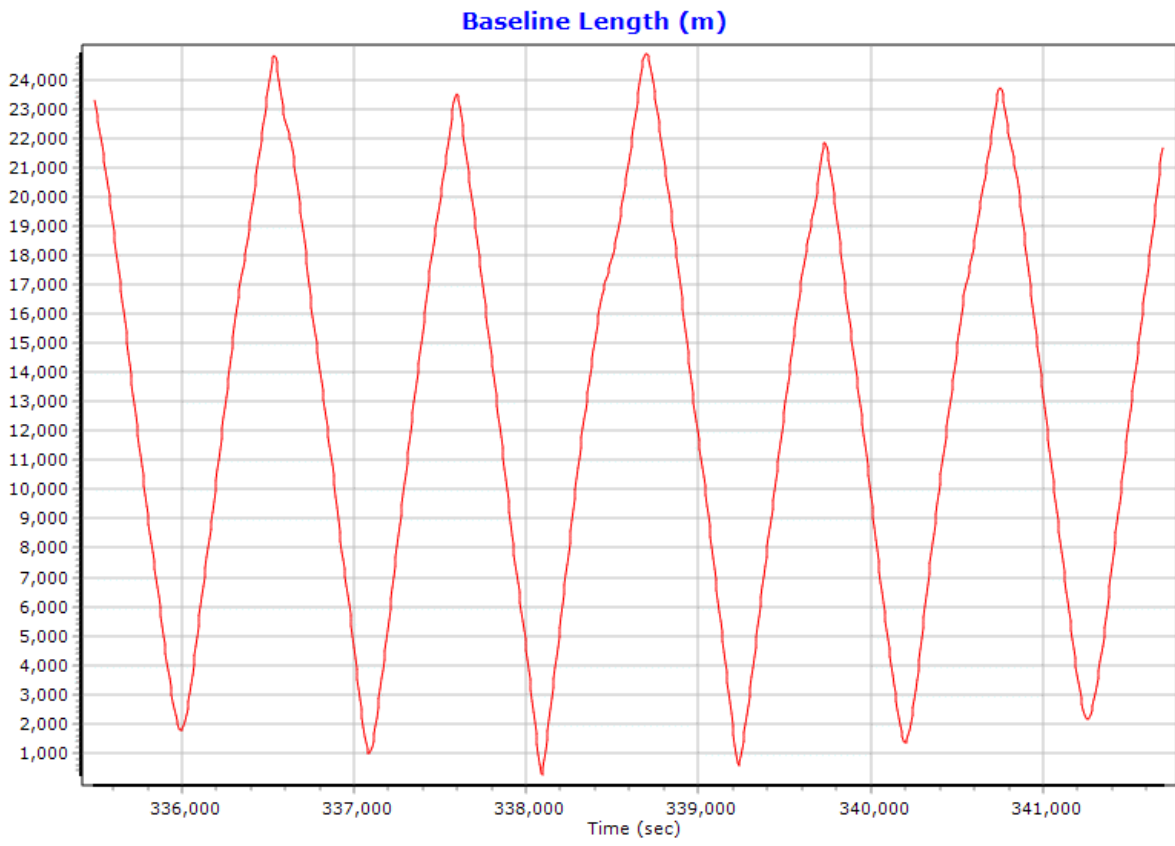
OK Cancel

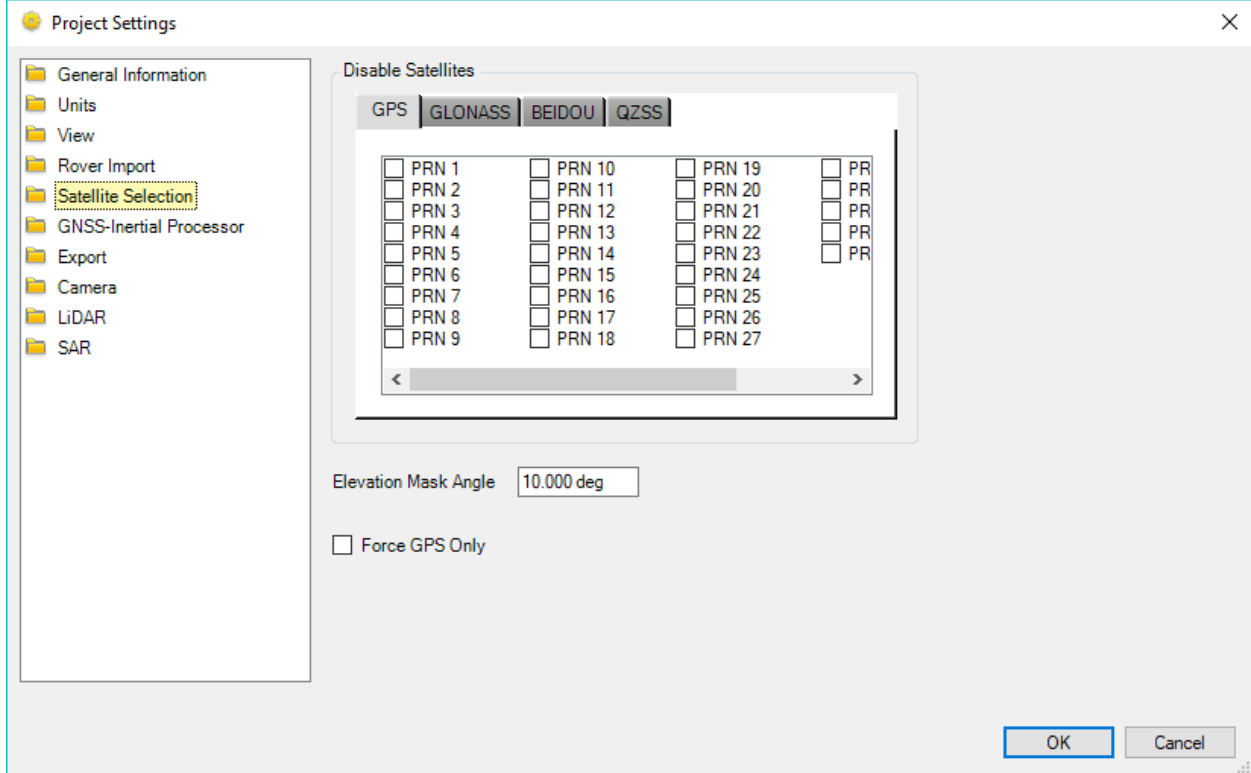
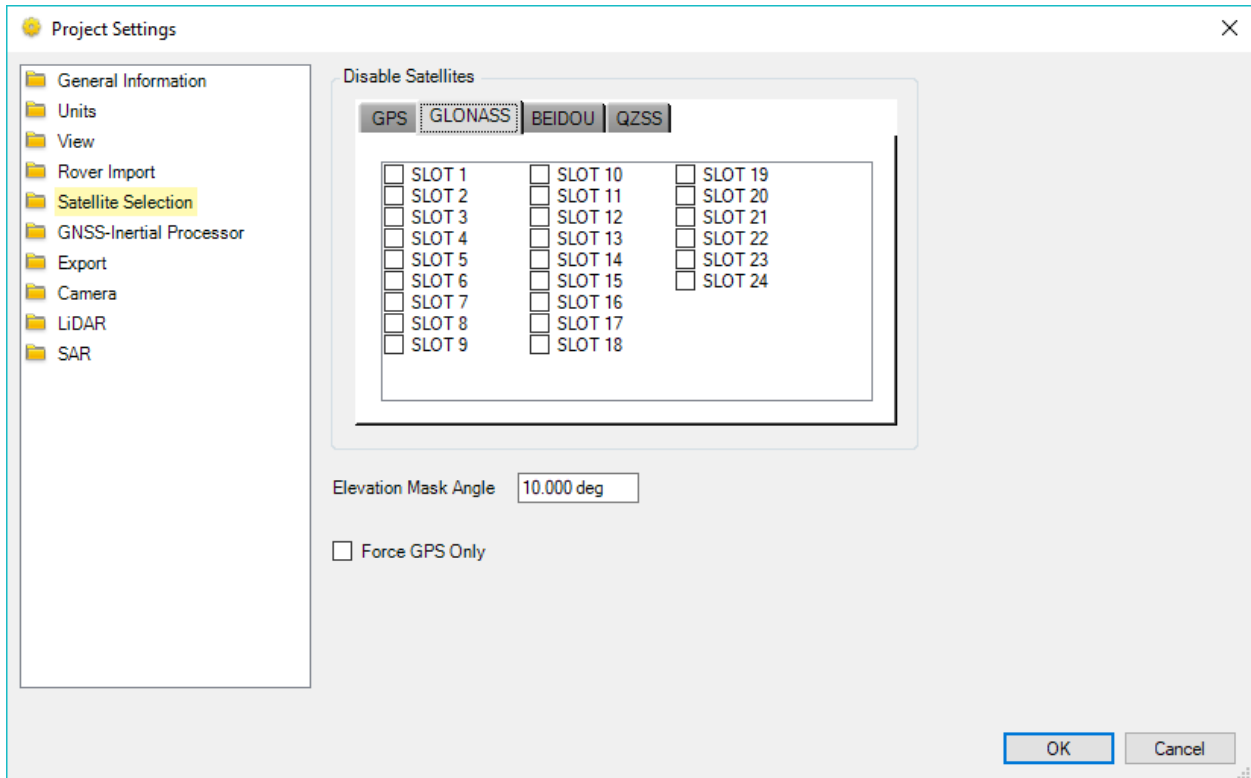
UNB18o8oB

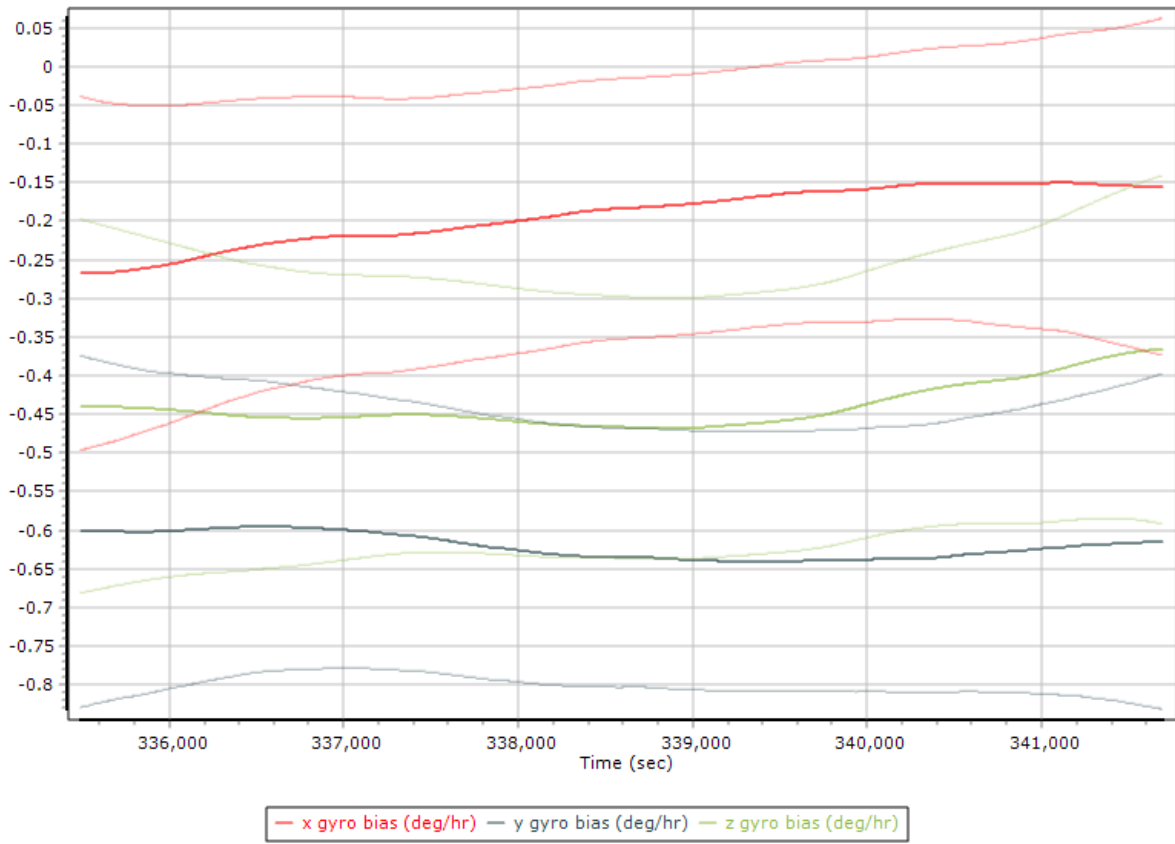


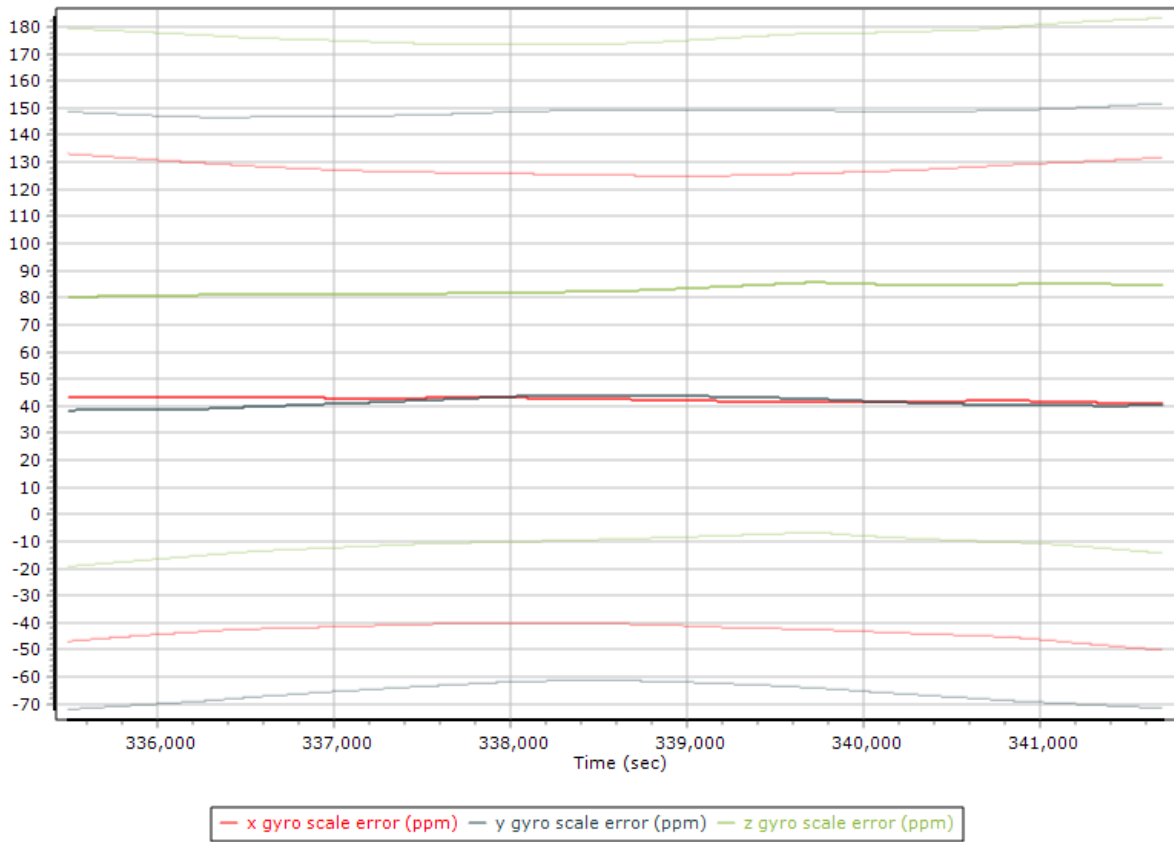












Project Settings

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

<3cm 10cm 50cm 1m 10m

Aircraft to Reference Mounting Angles

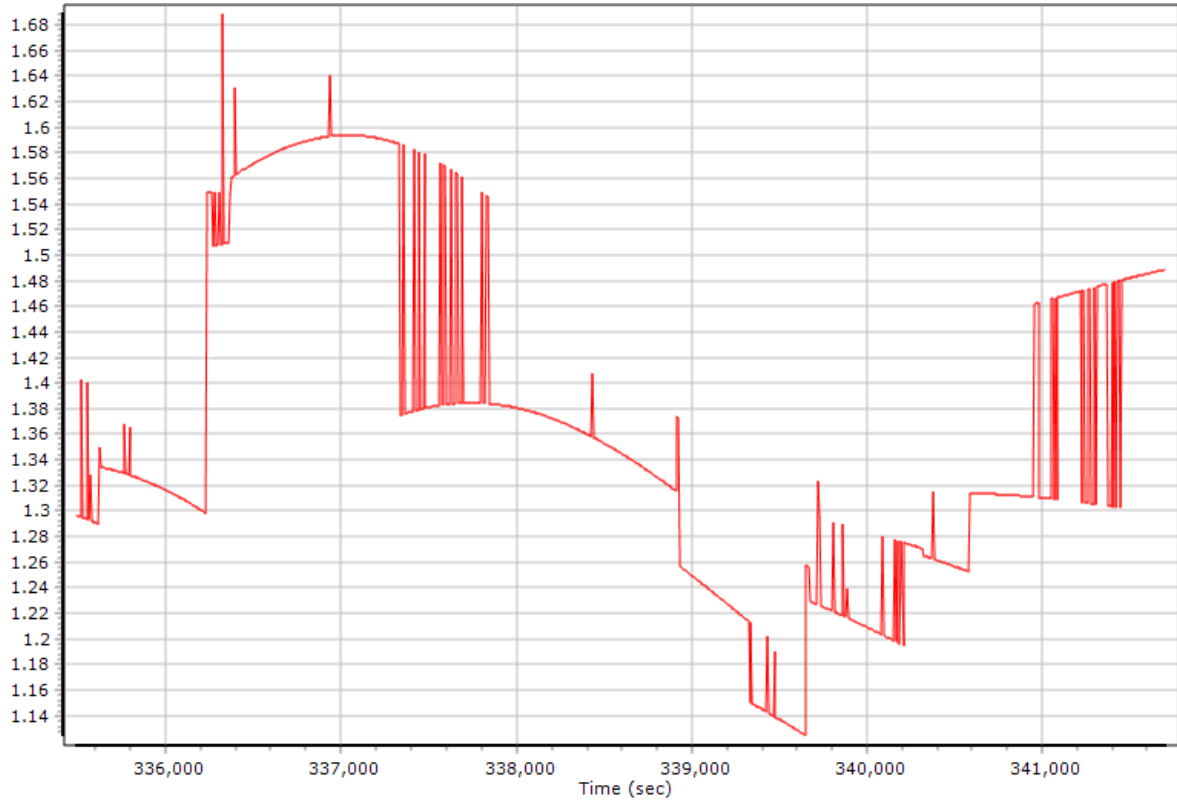
X:

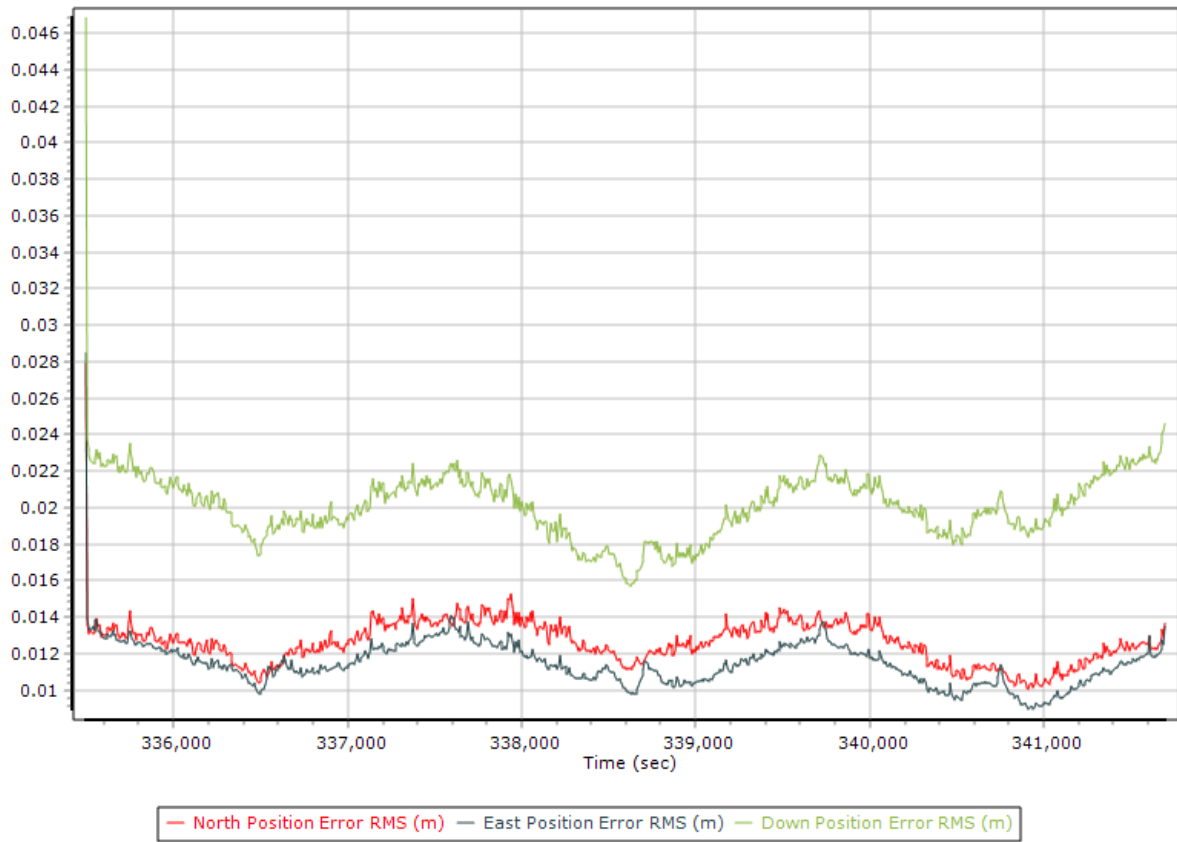
Y:

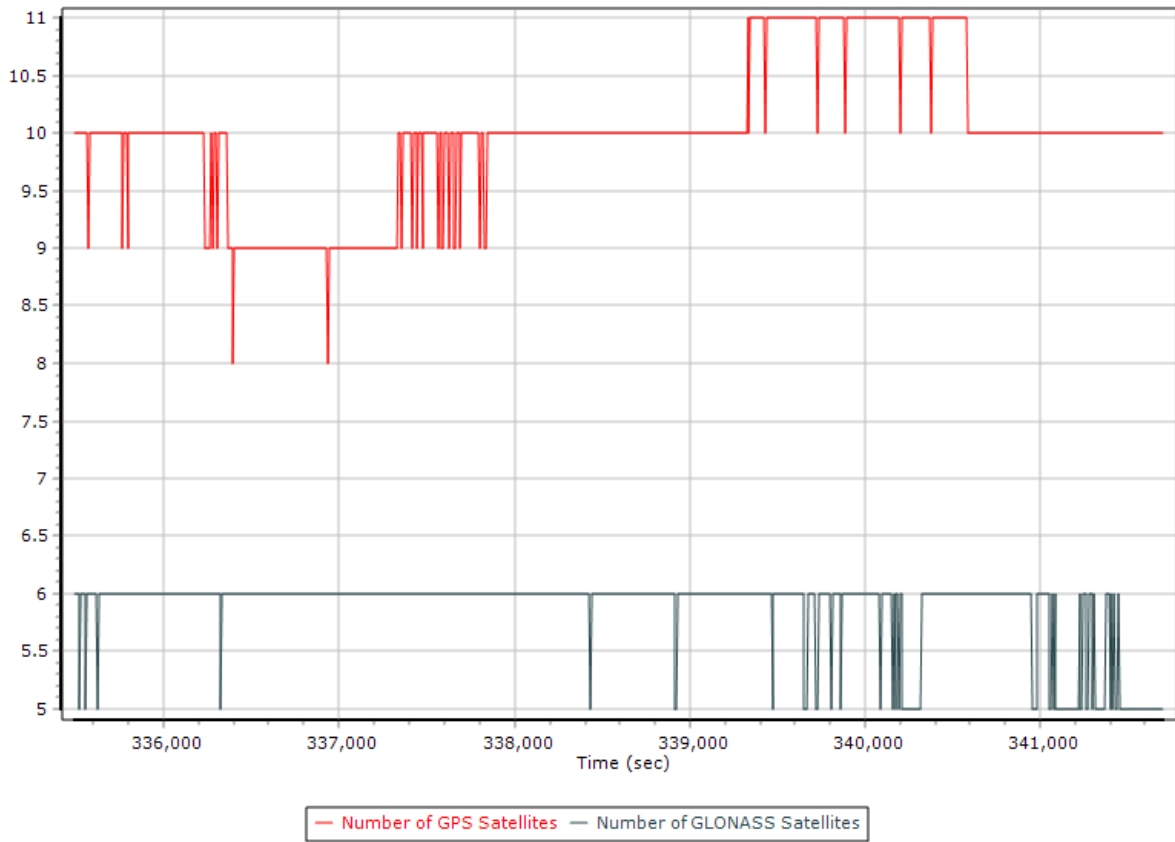
Z:

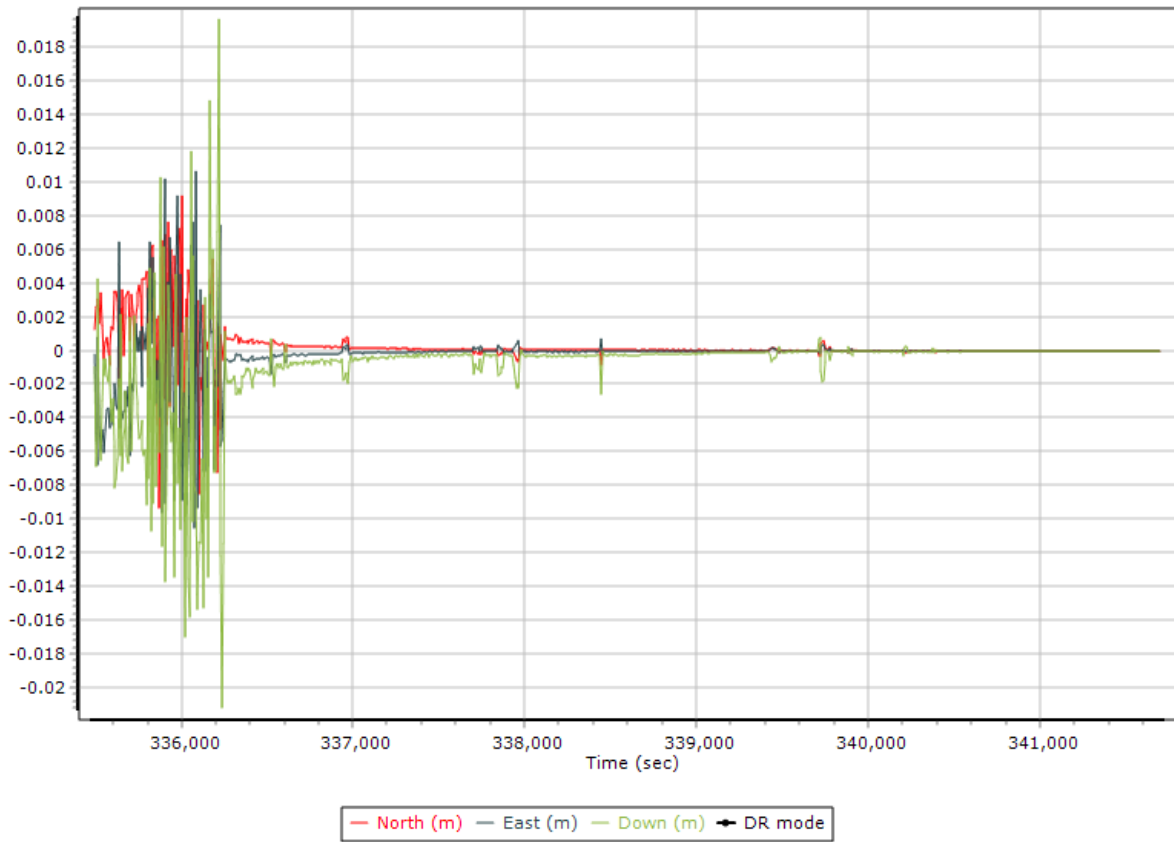
OK Cancel

PDOP









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: 335490.942
End: 341704.284

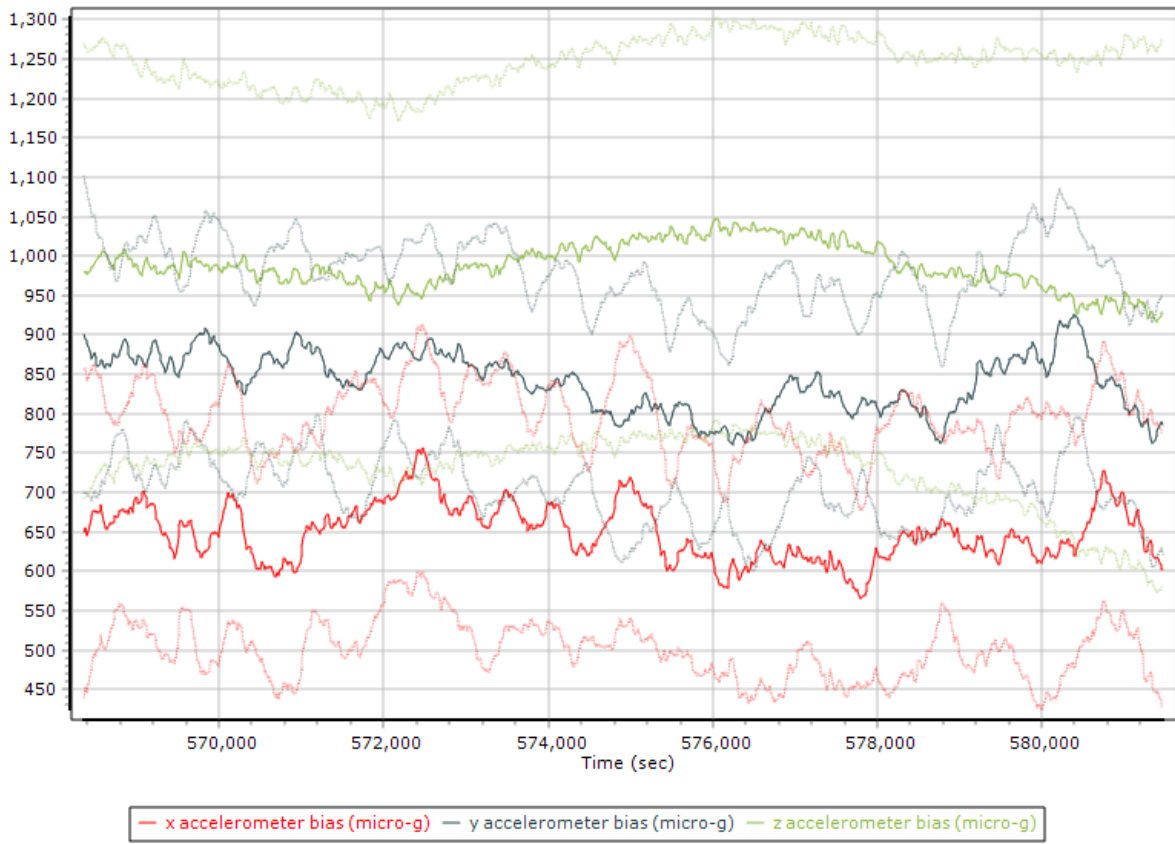
Entire time interval
 Seconds of start week

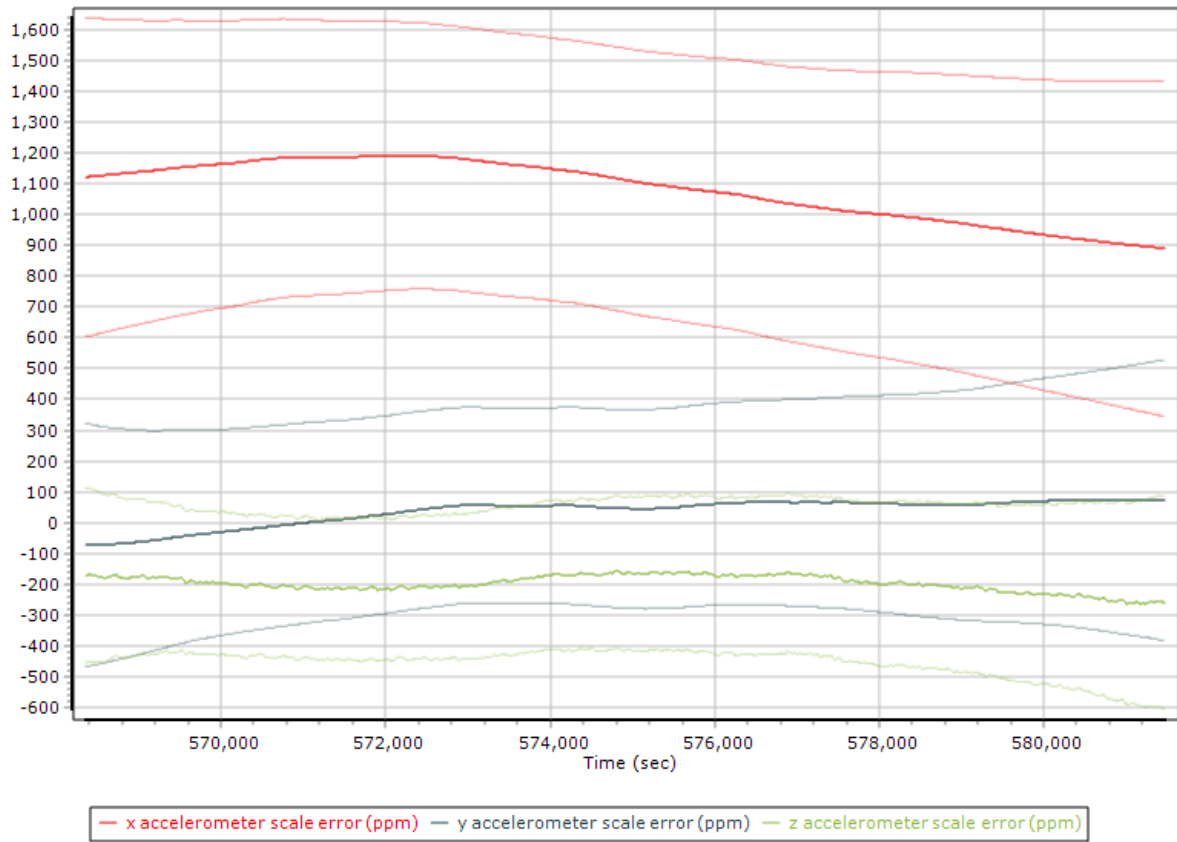
UTC Offset: 18.000

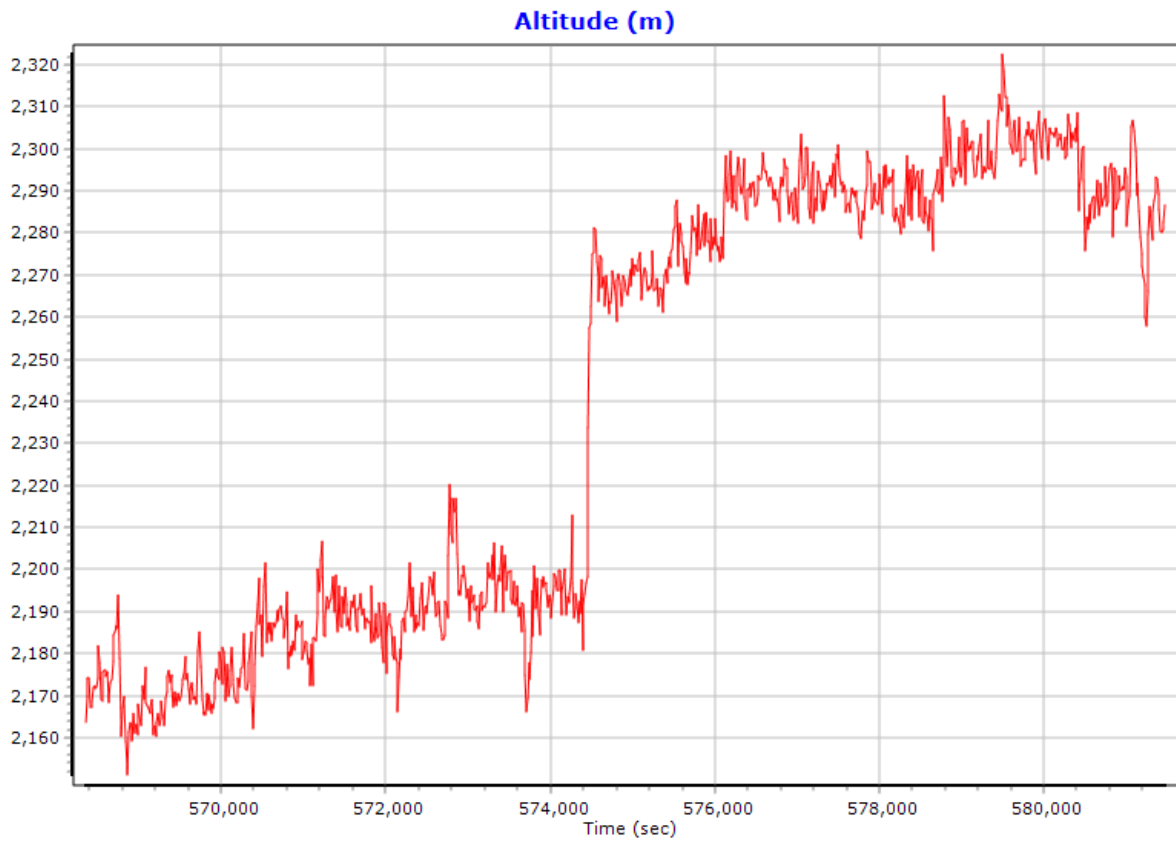
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

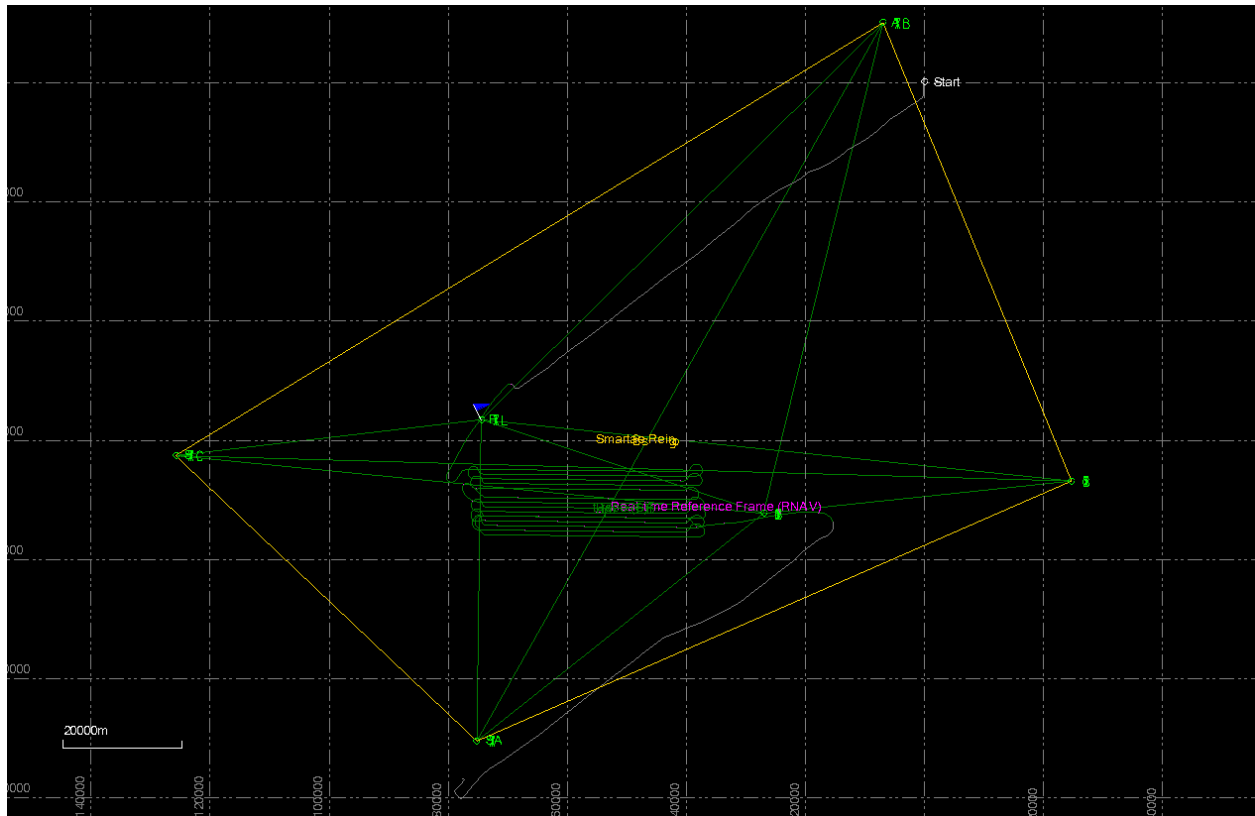
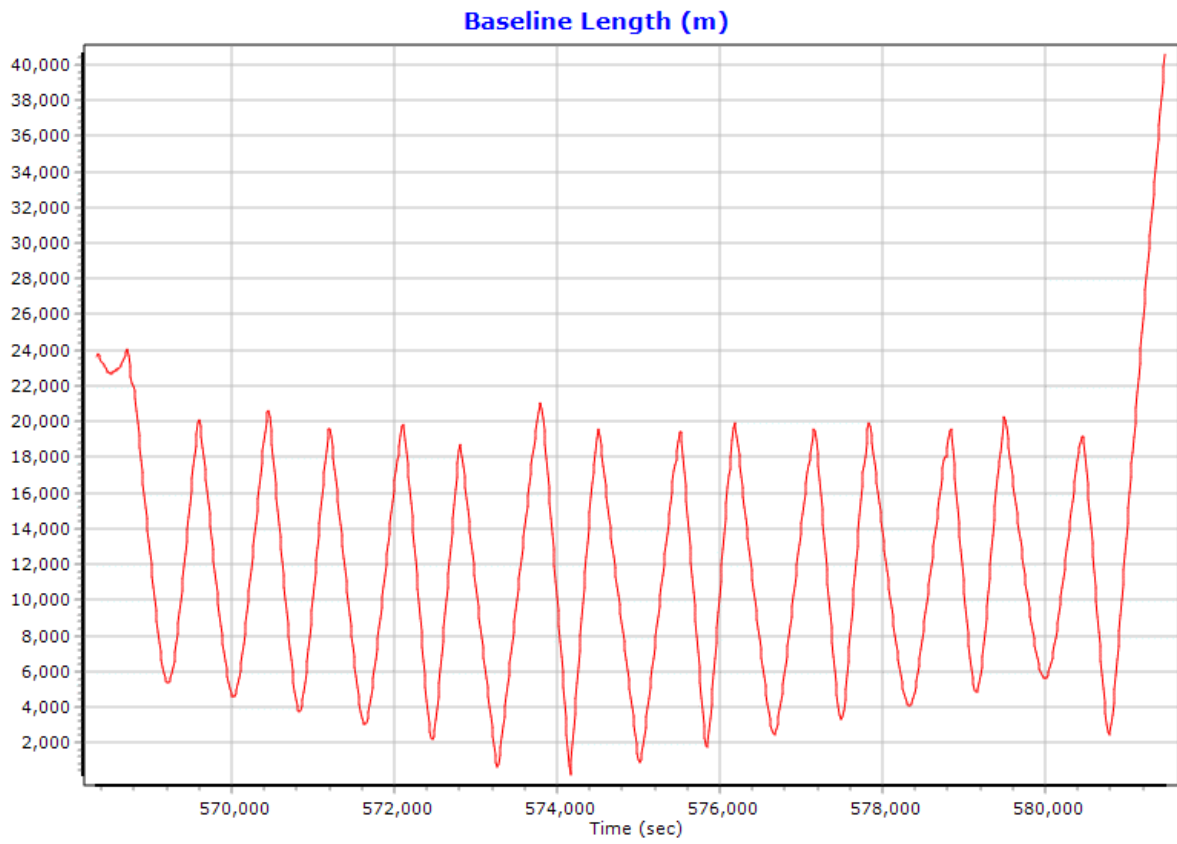
OK Cancel

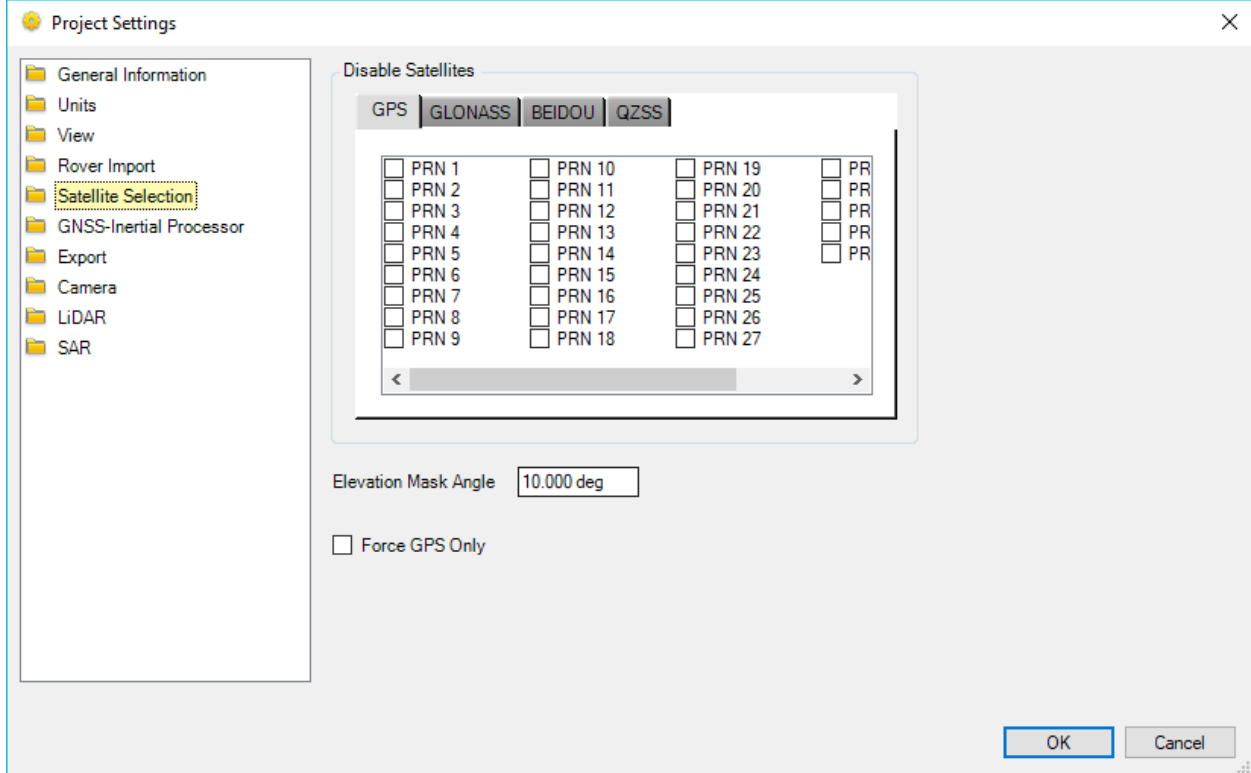
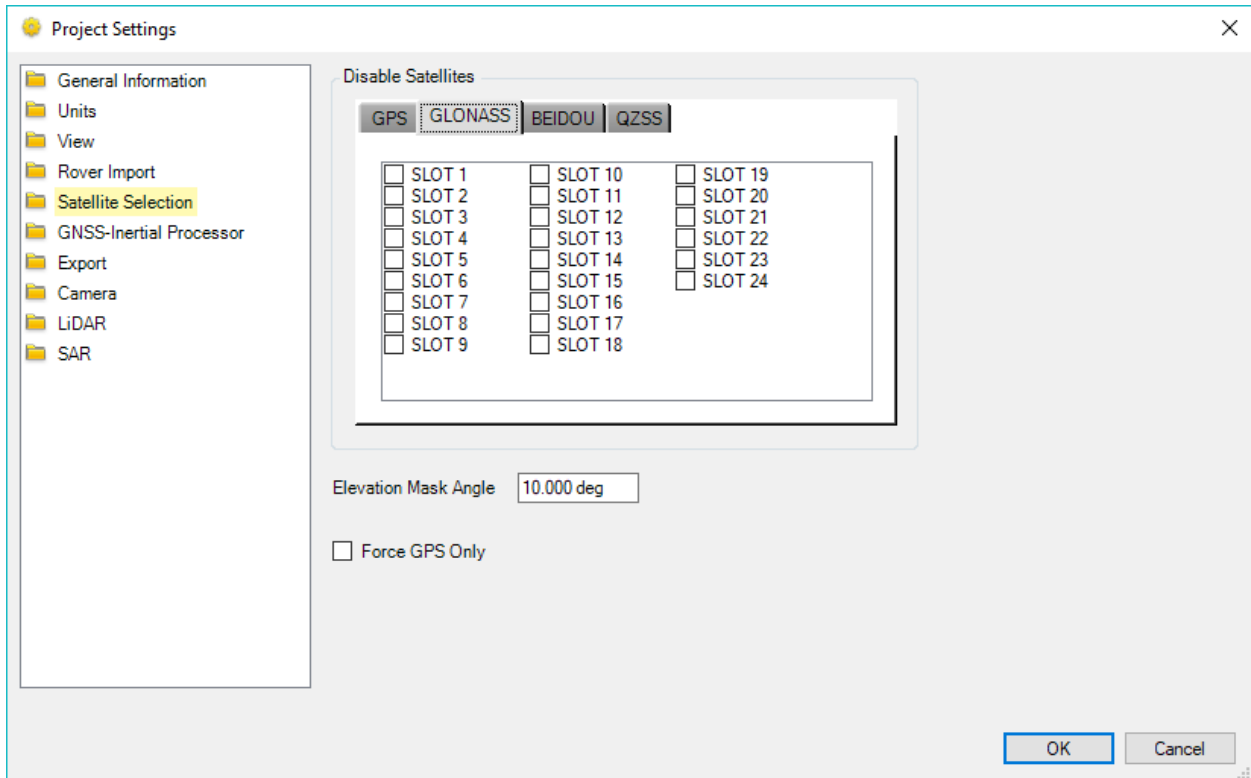
UNB18083A

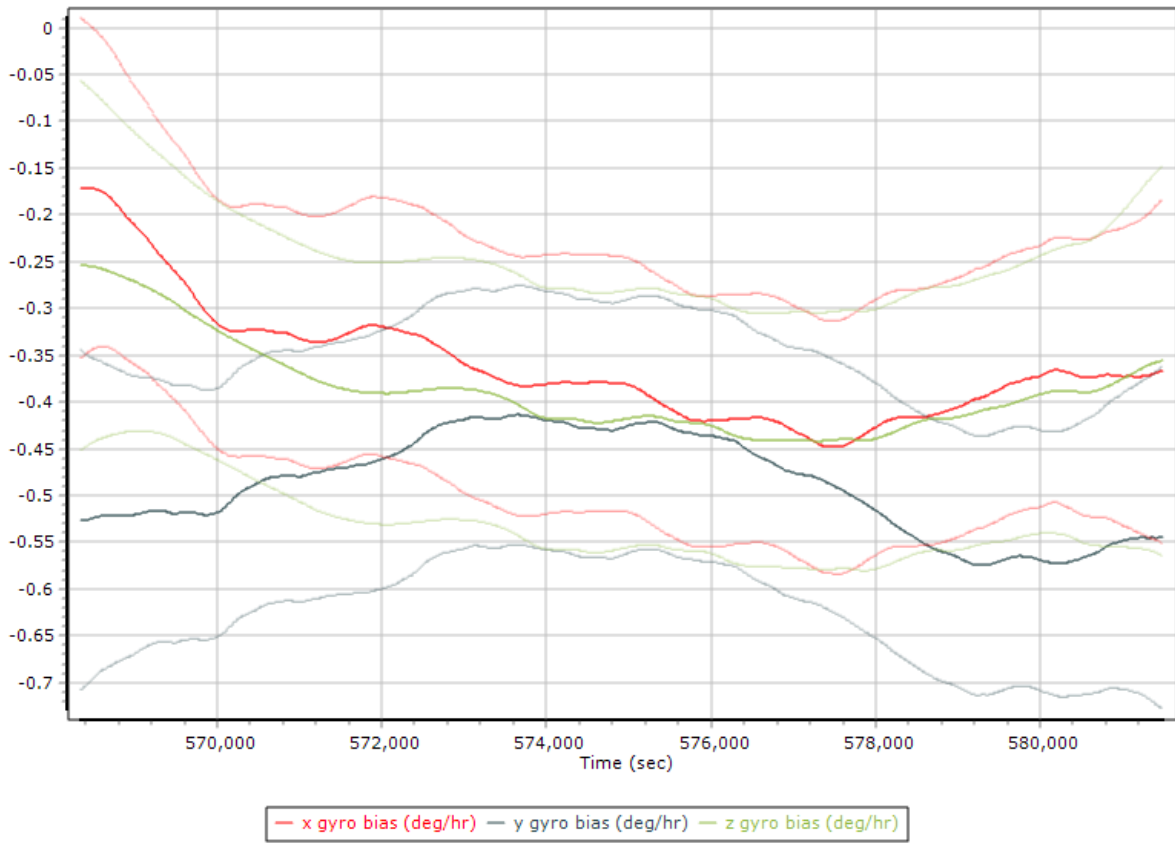


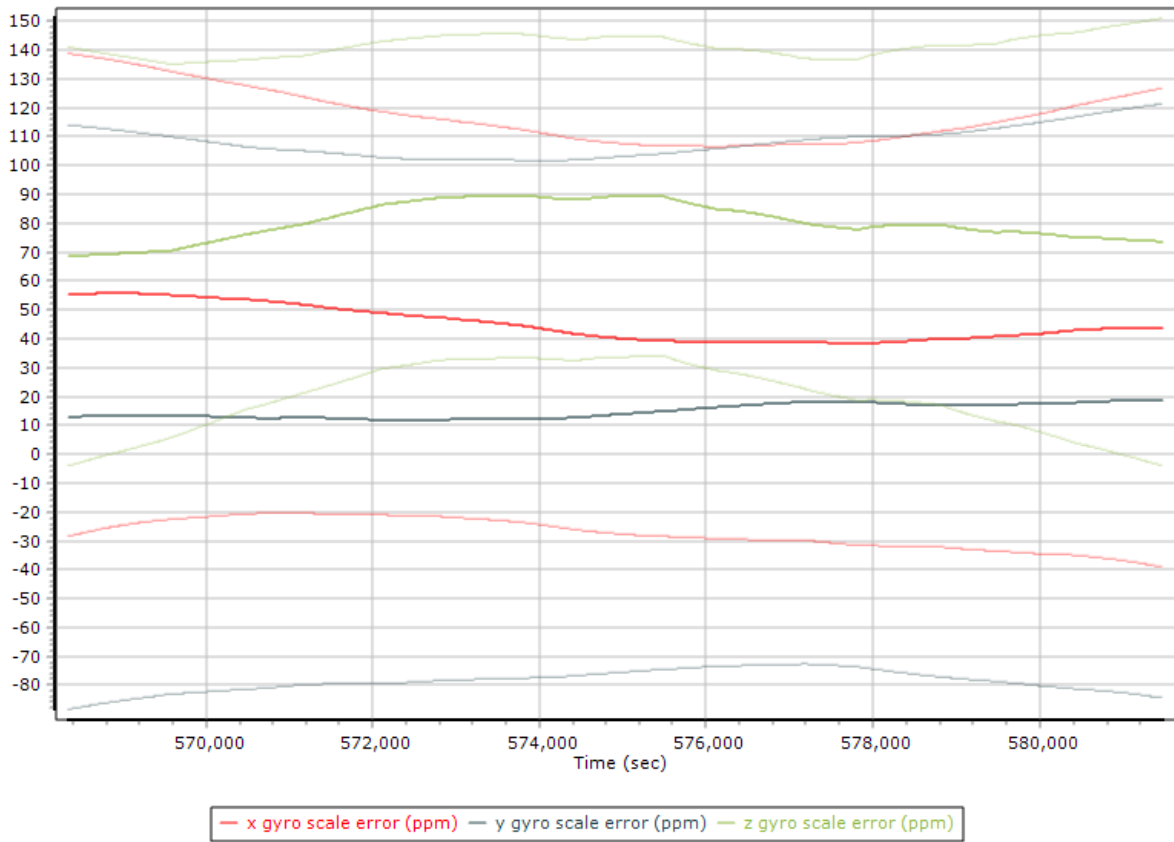












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

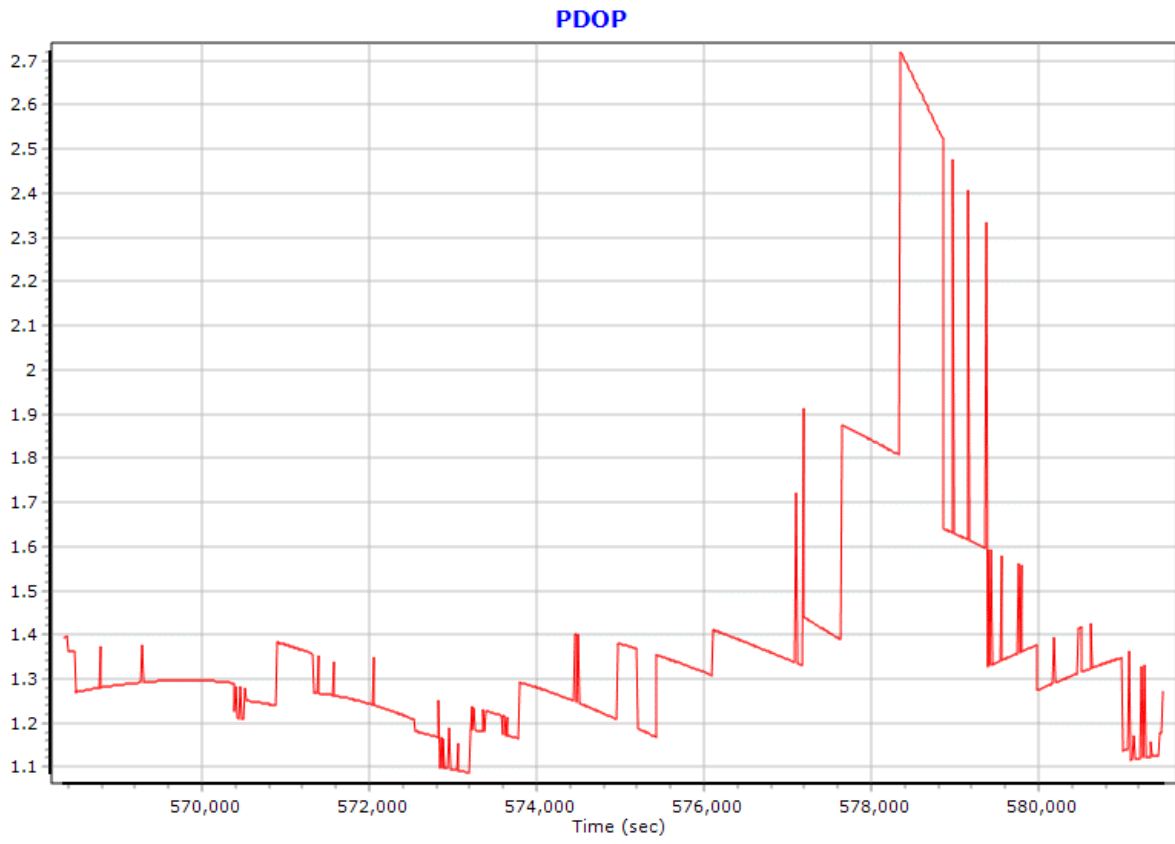
<3cm 10cm 50cm 1m 10m

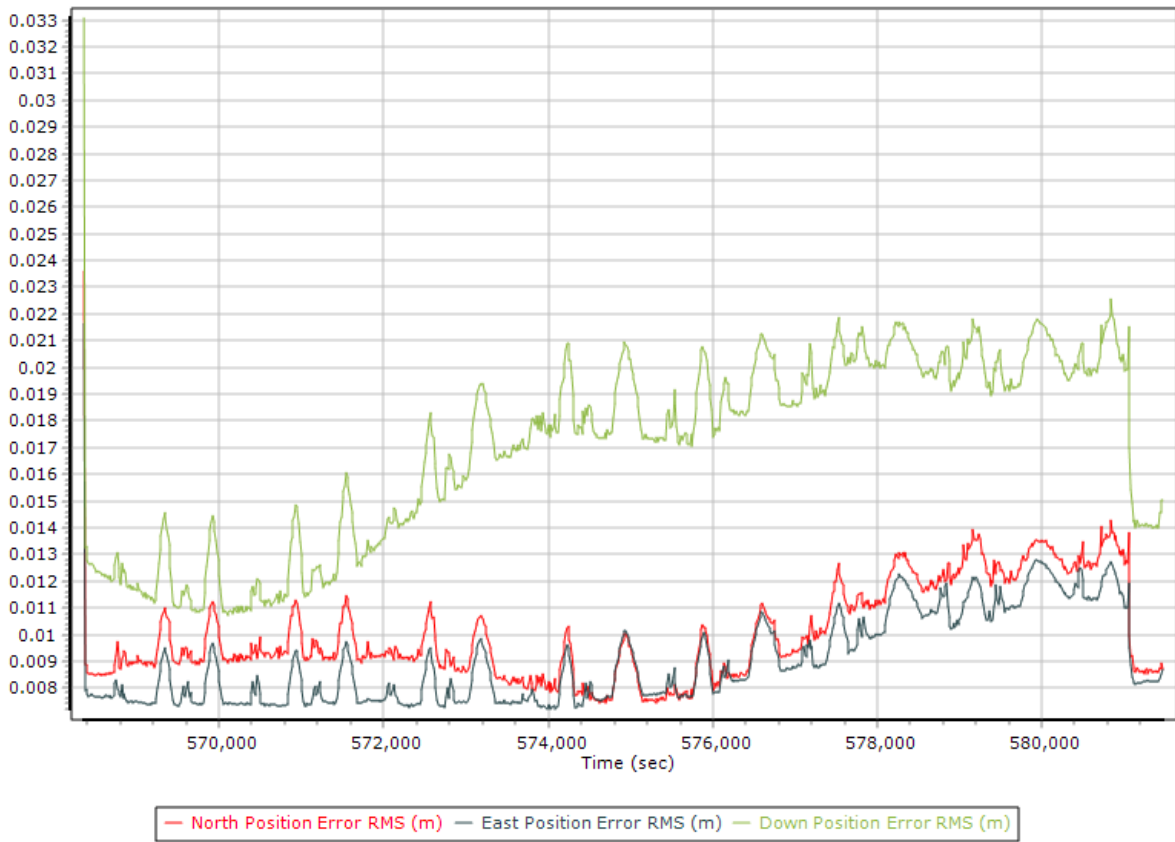
Aircraft to Reference Mounting Angles

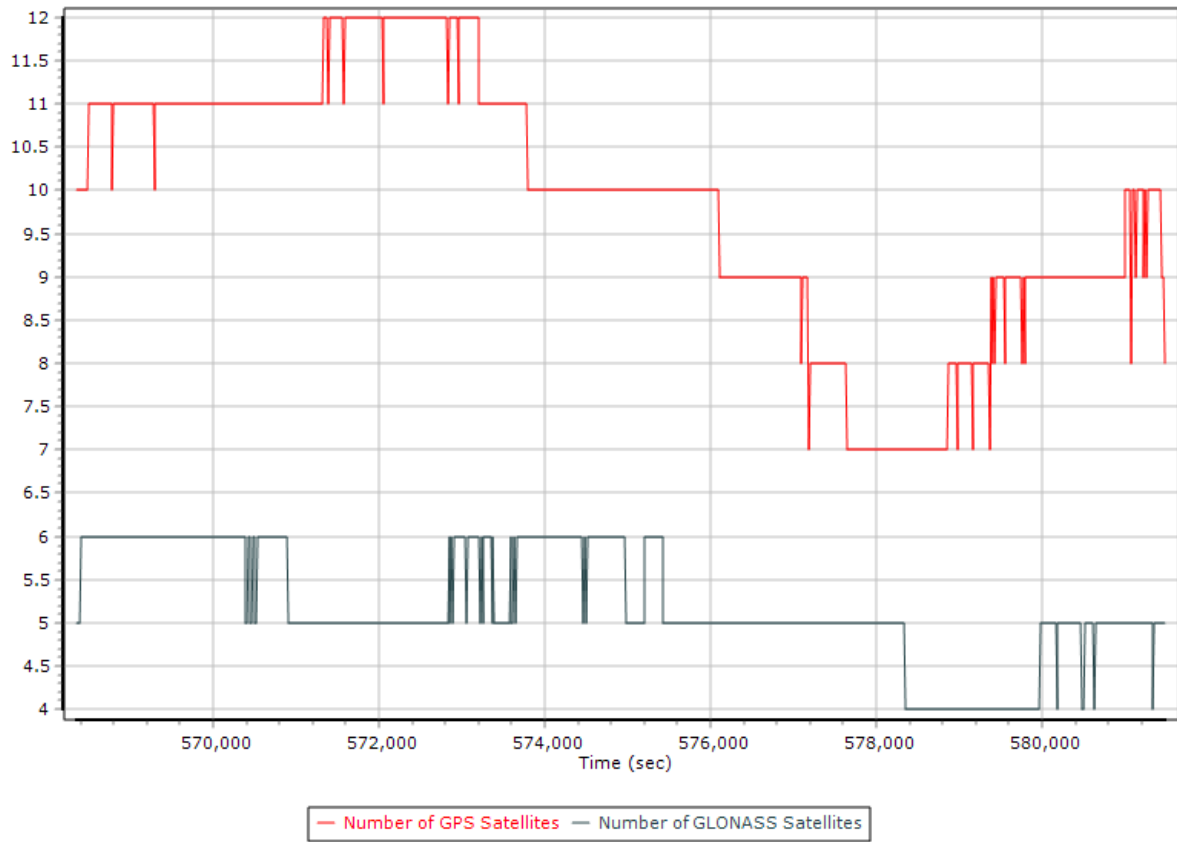
X:

Y:

Z:









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: 568345.482
End: 581502.982

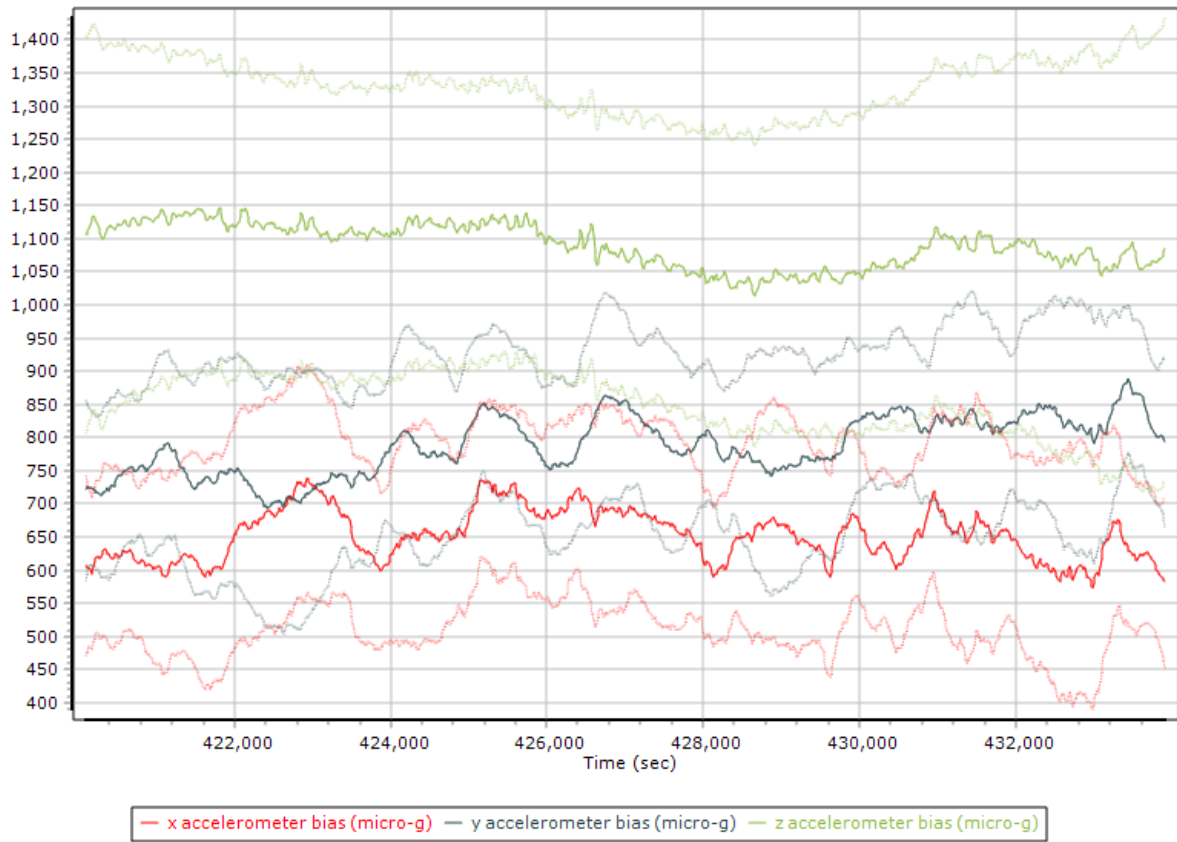
Entire time interval
 Seconds of start week

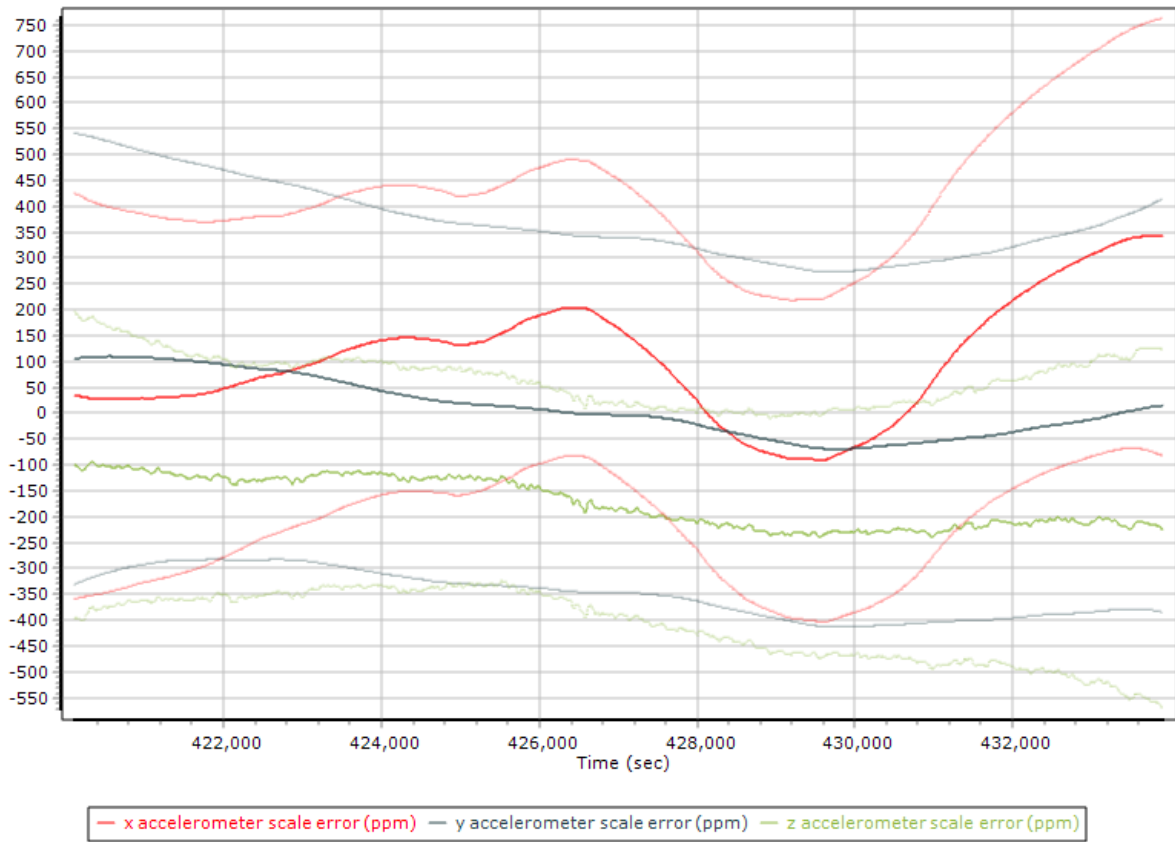
UTC Offset: 18.000

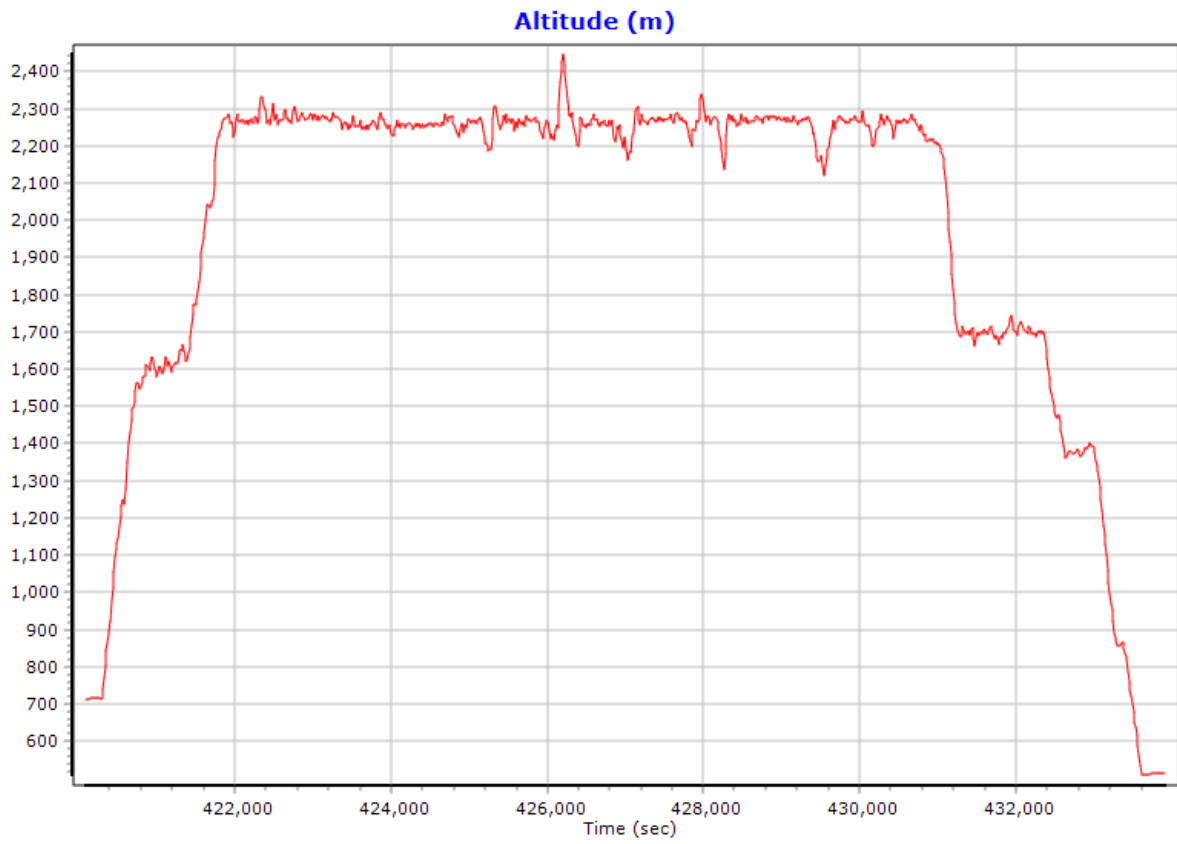
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

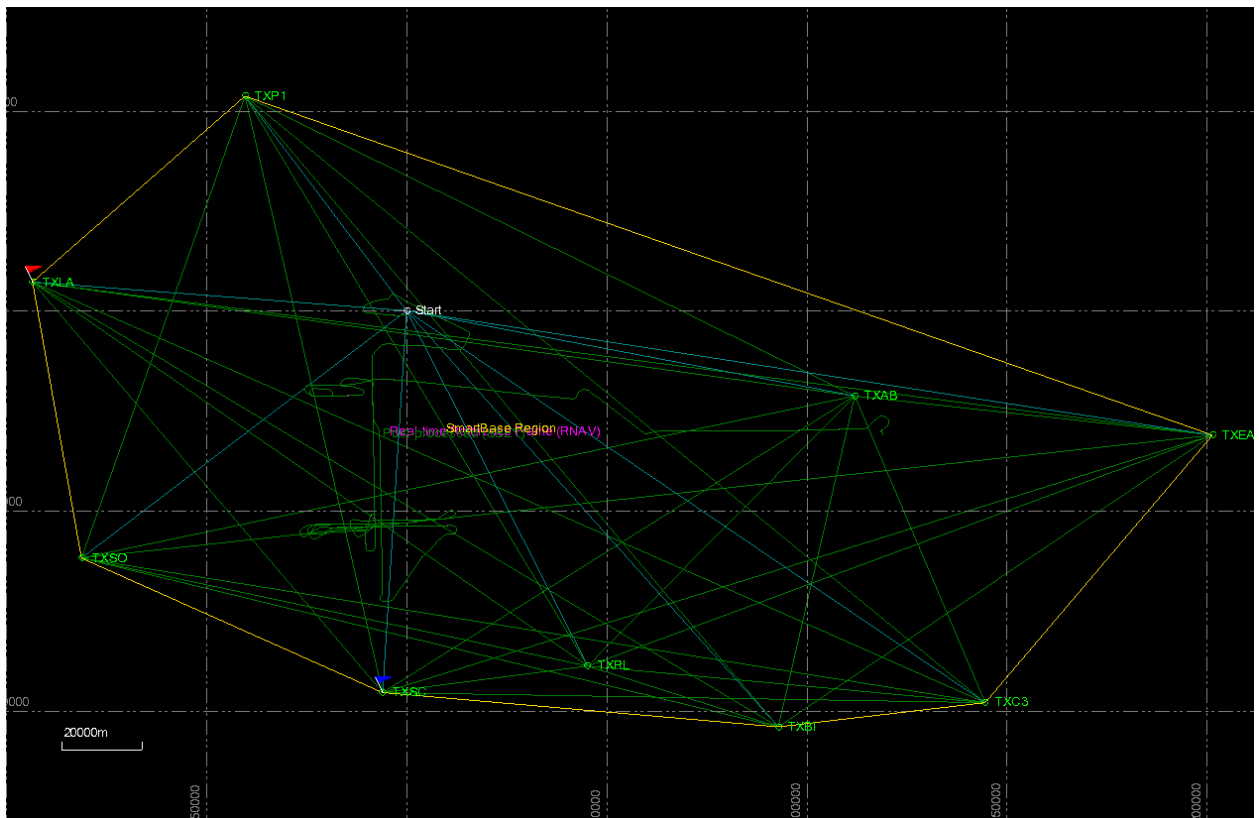
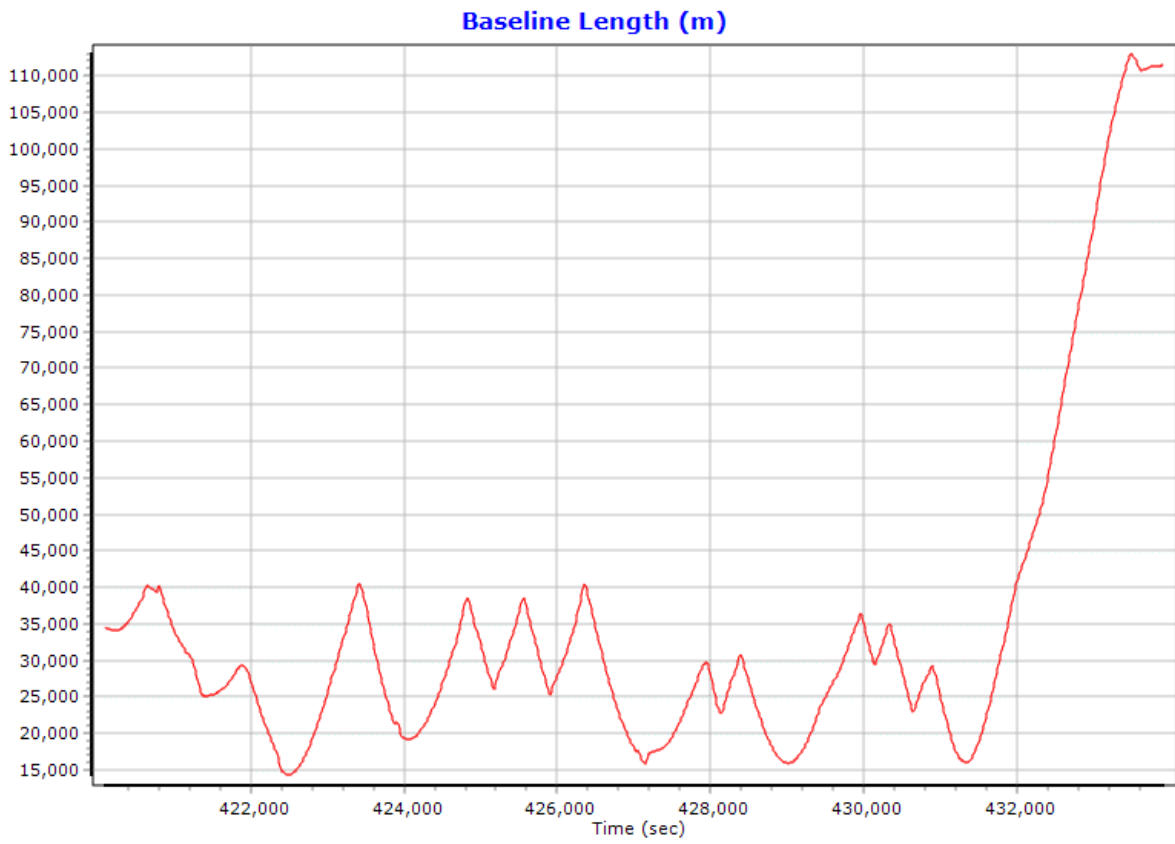
OK Cancel

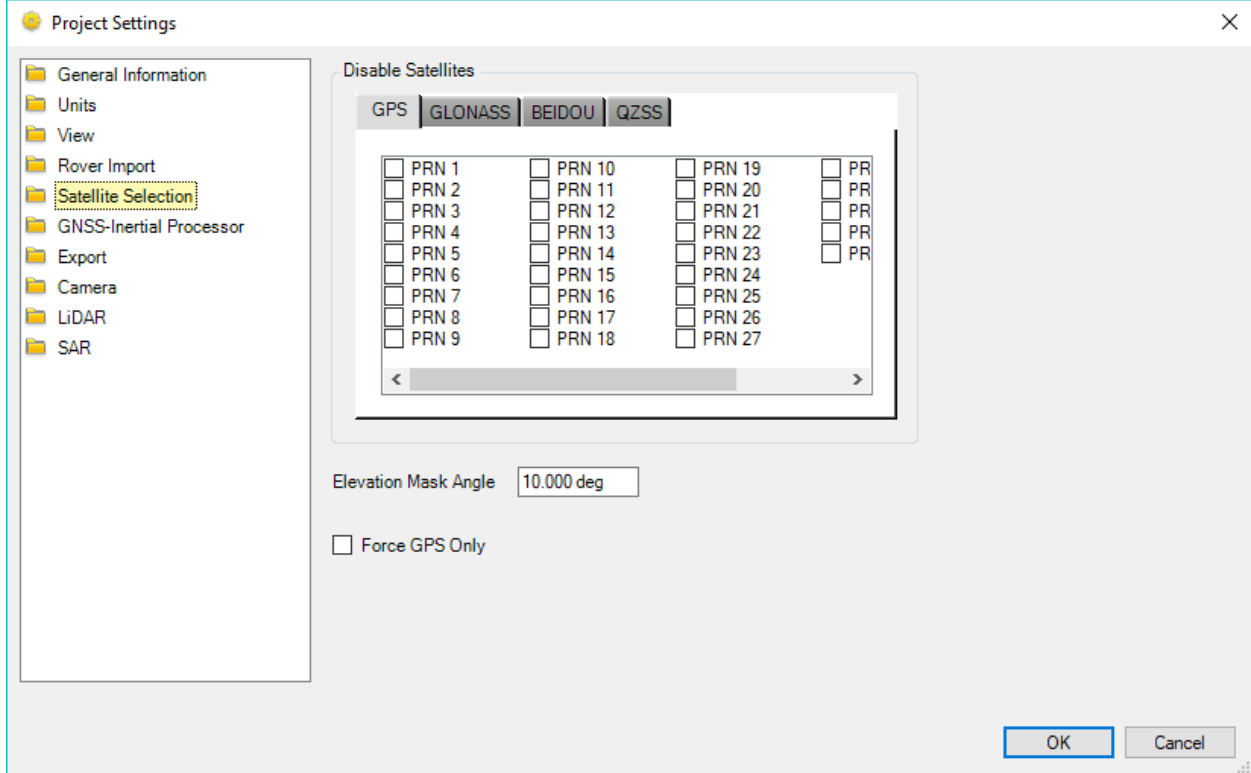
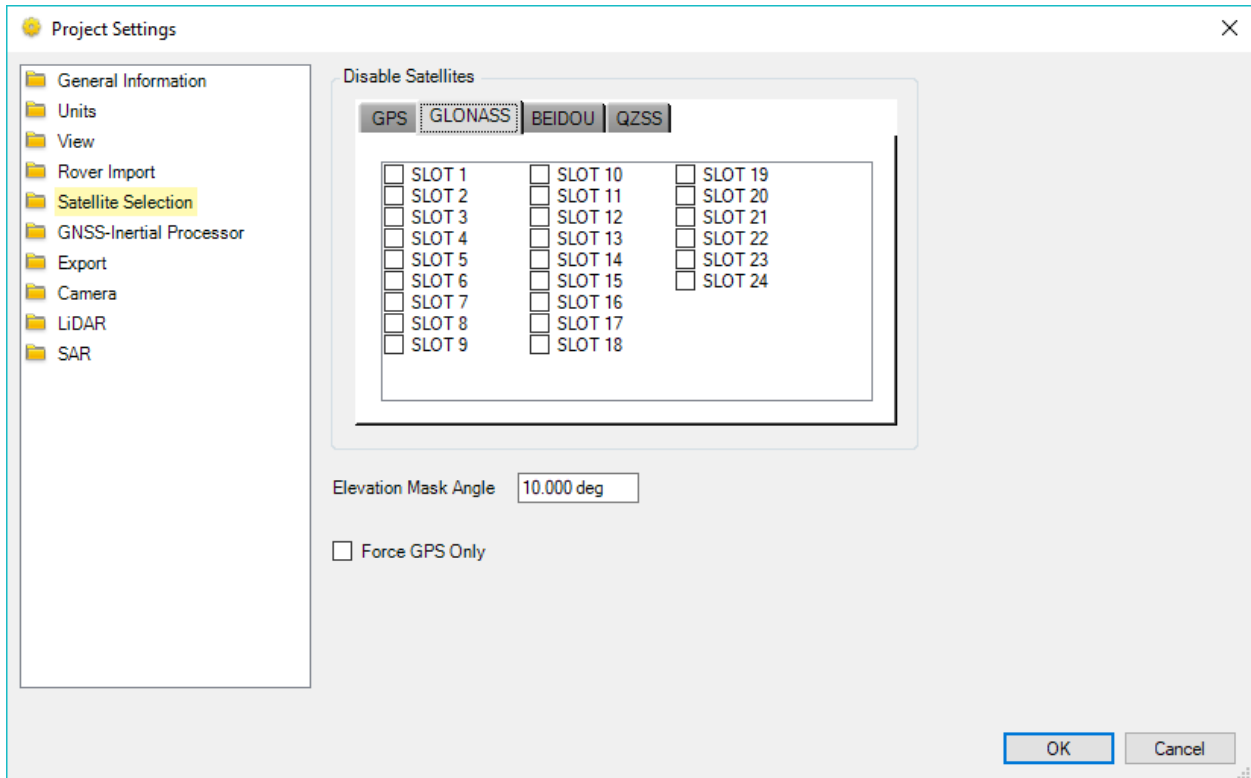
UNB18095B

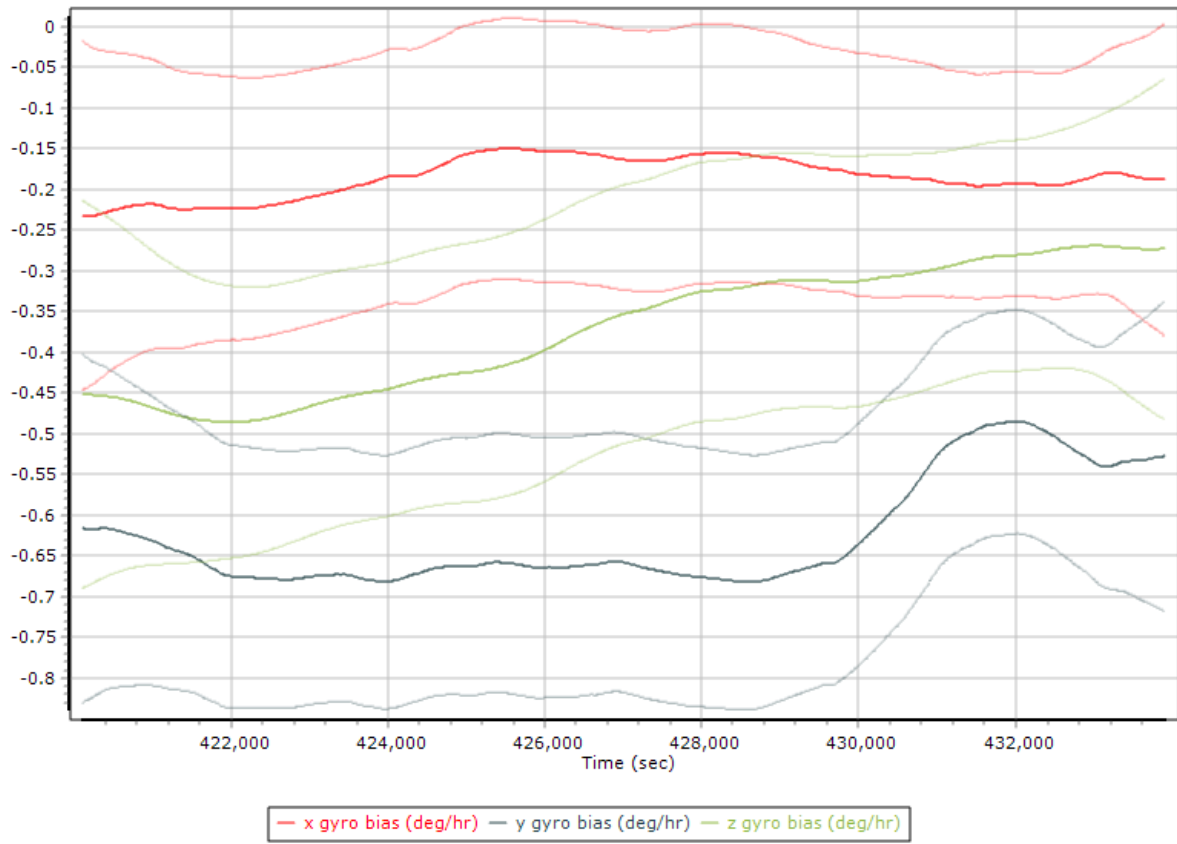


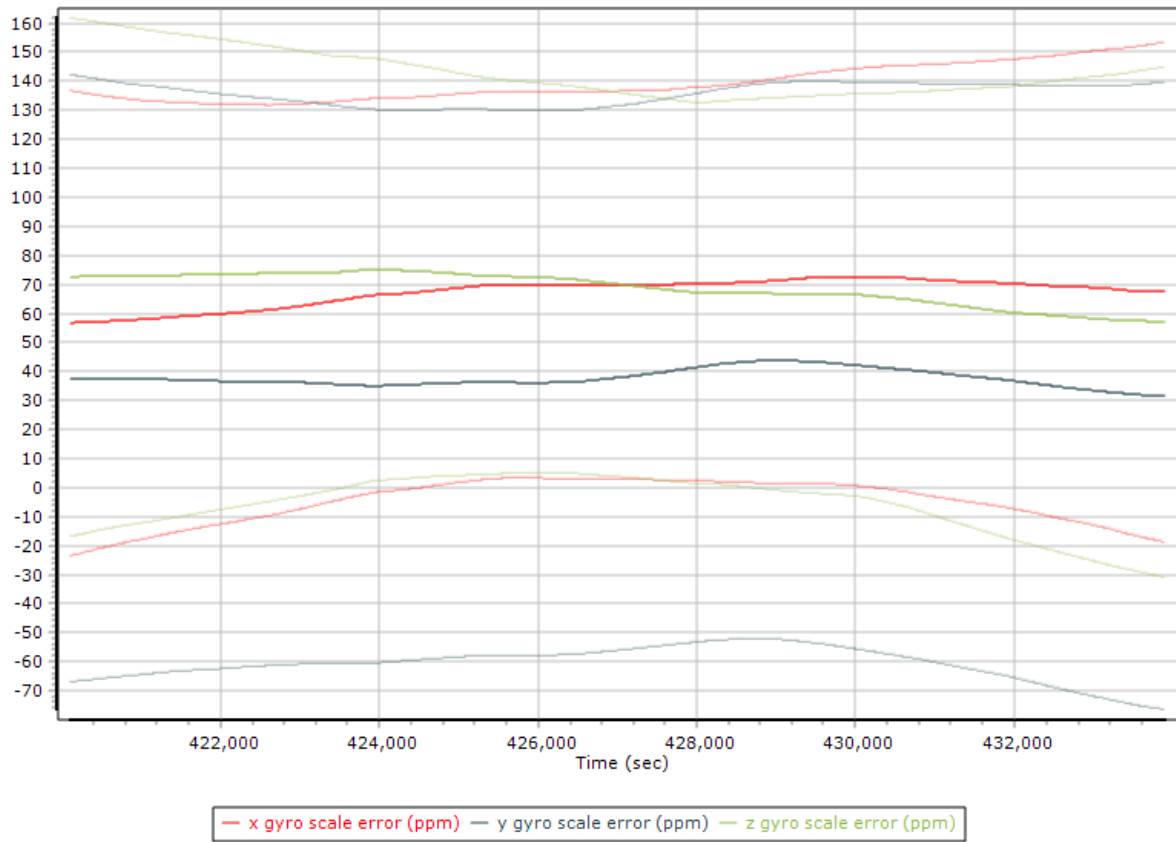












Project Settings ✕

- 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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Standard Deviation:

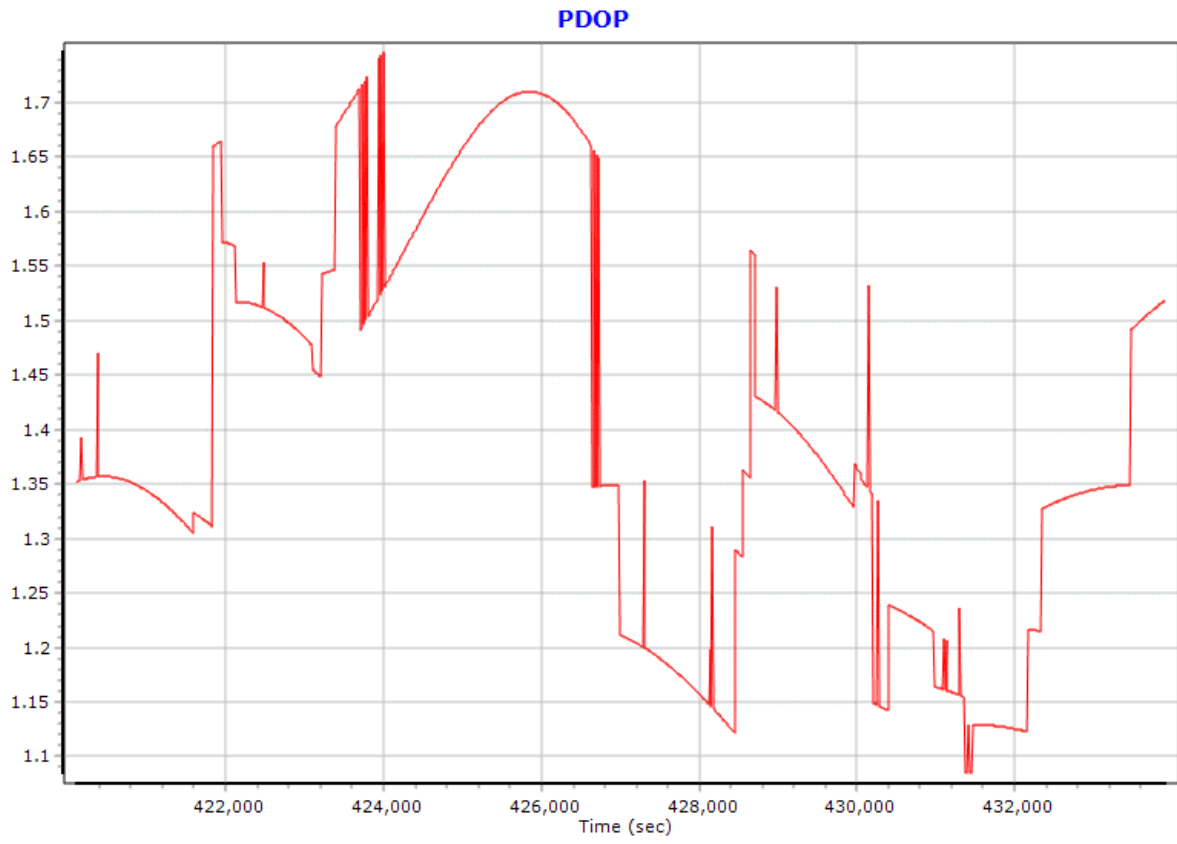
<3cm 10cm 50cm 1m 10m

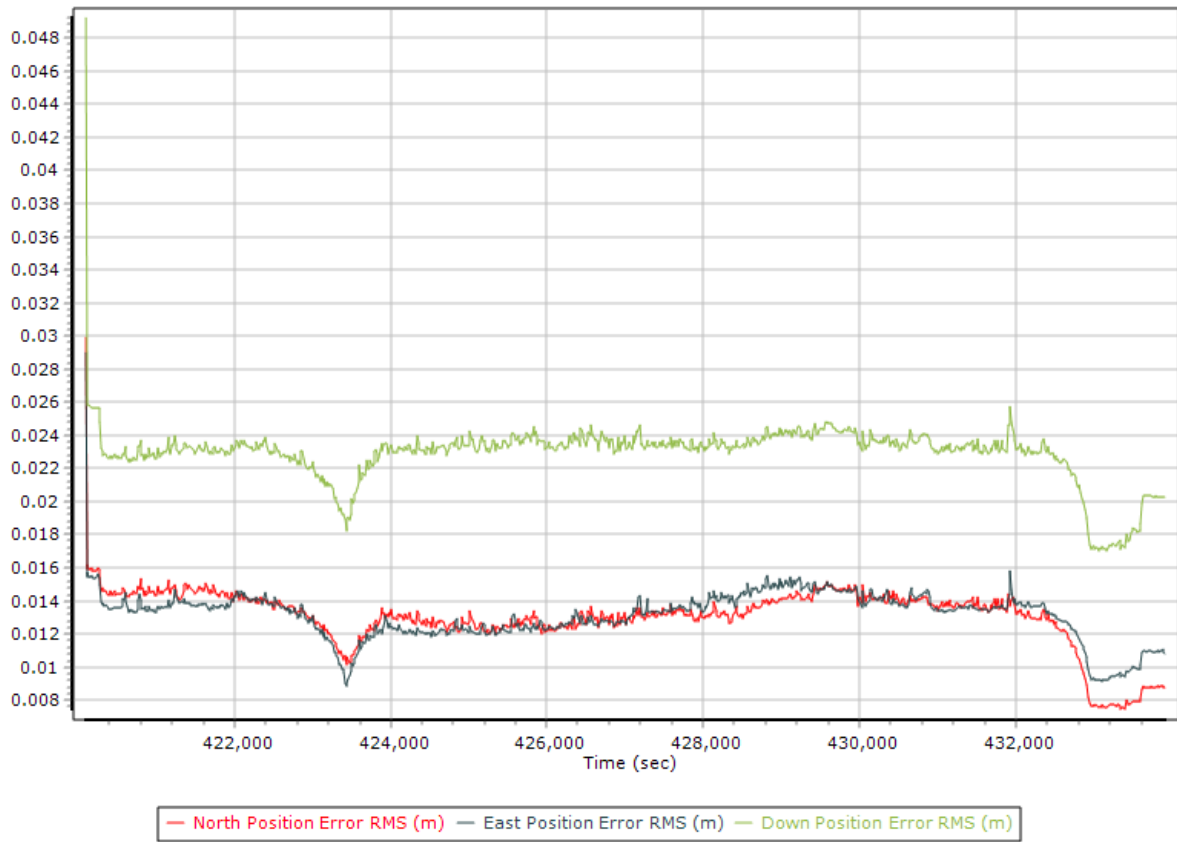
Aircraft to Reference Mounting Angles

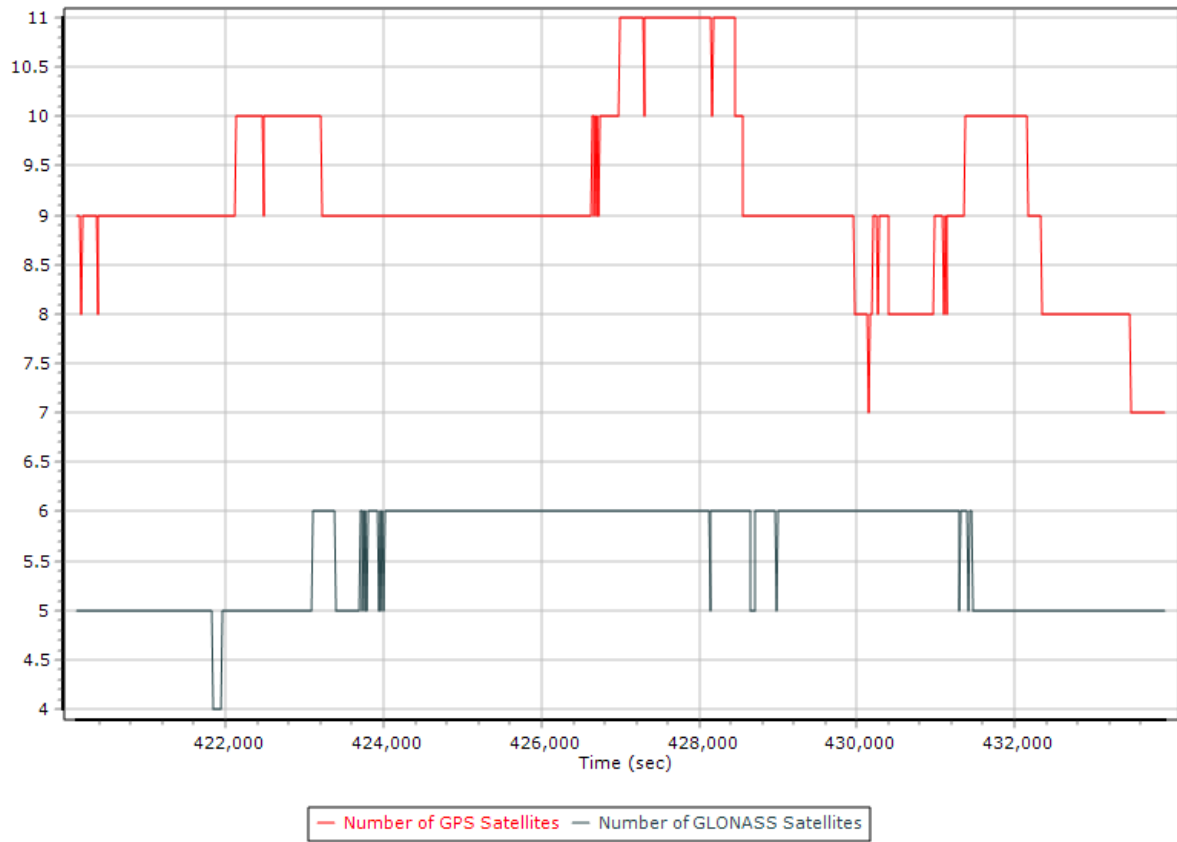
X:

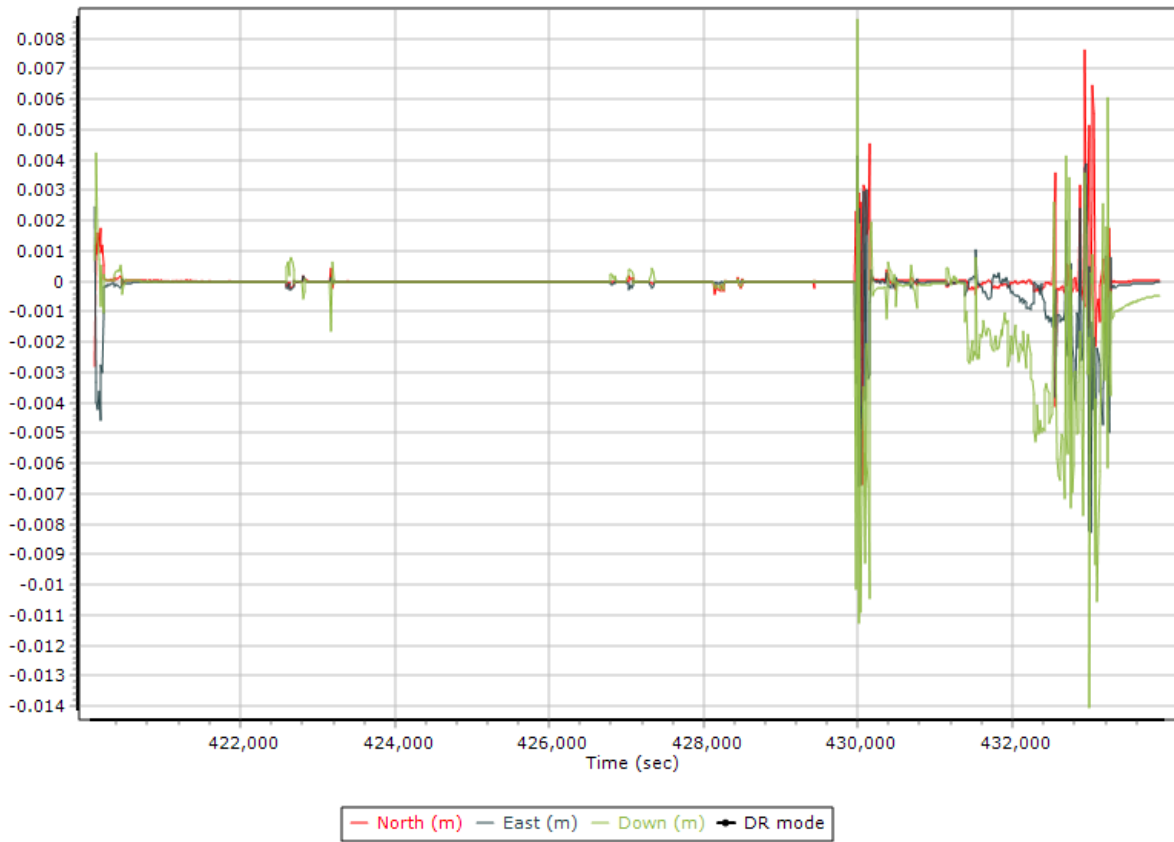
Y:

Z:









Project Settings [X]

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

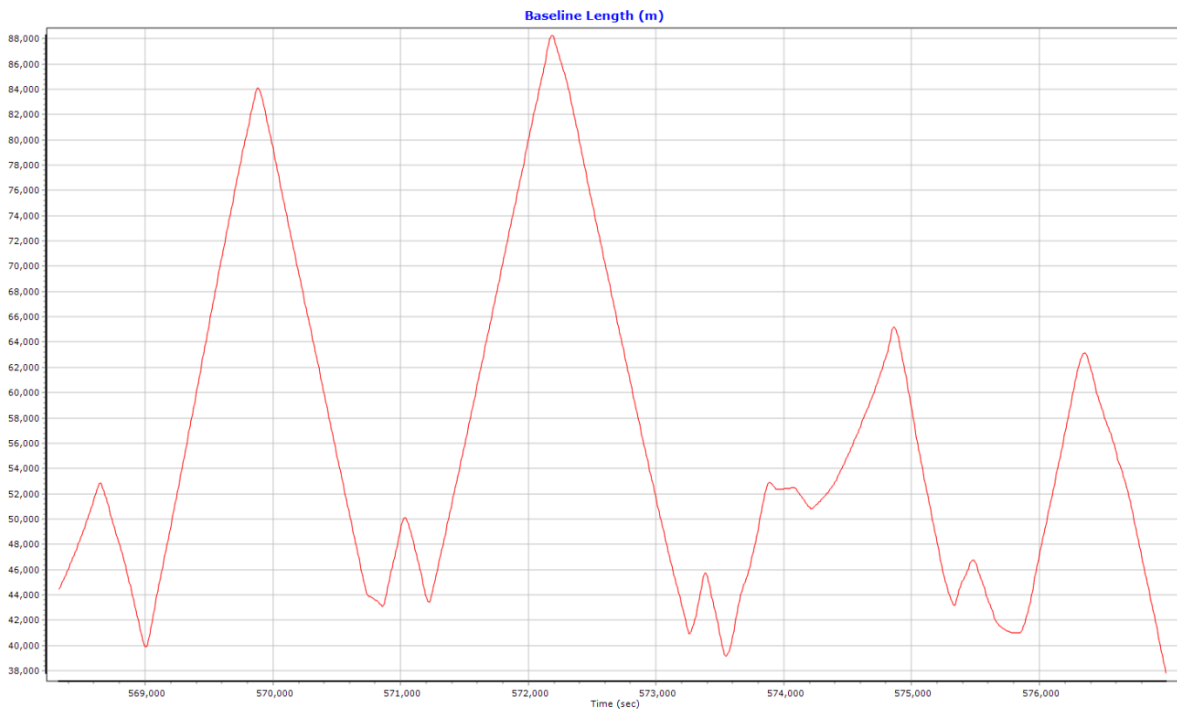
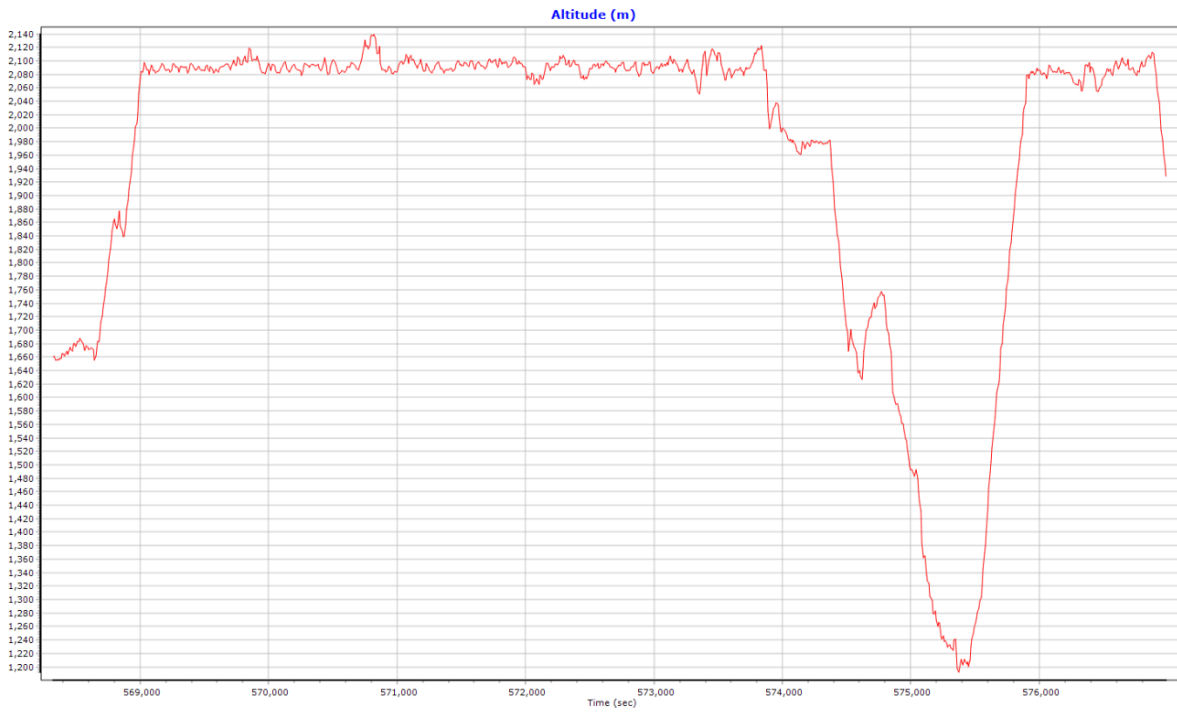
Timing

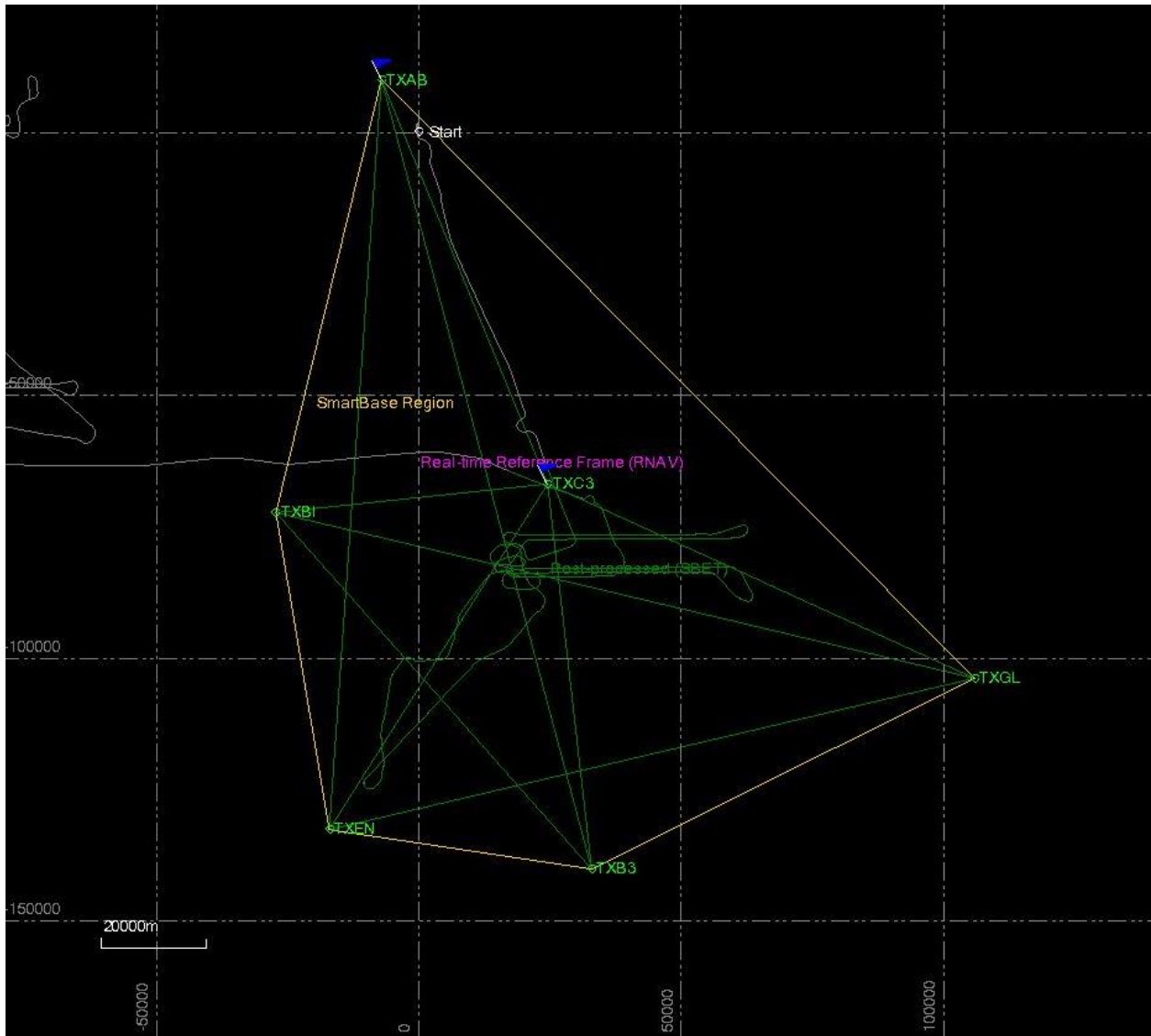
Start: 419766.000
 End: 433928.000
 Entire time interval
 Seconds of start week
 UTC Offset: 18.000

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

OK Cancel

UNB18118A







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:

Y:

Z:

Reference to IMU Mounting Angles

X:

Y:

Z:

Reference to Primary GNSS Lever Arm

X:

Y:

Z:

Aircraft to Reference Mounting Angles

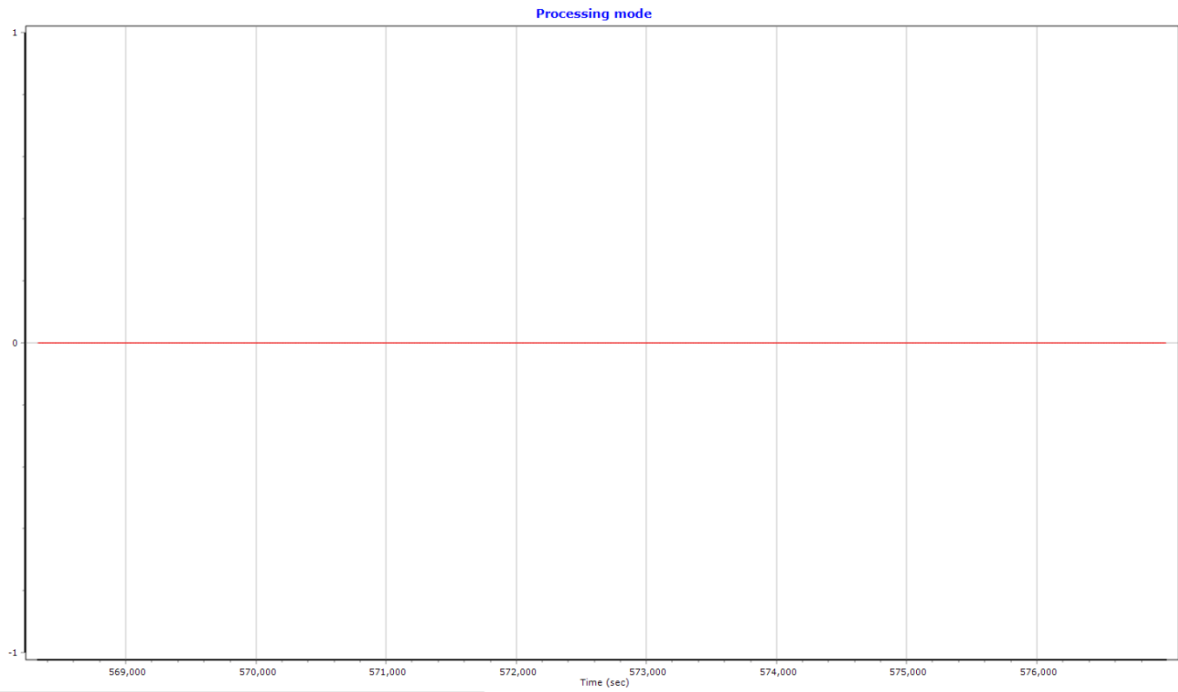
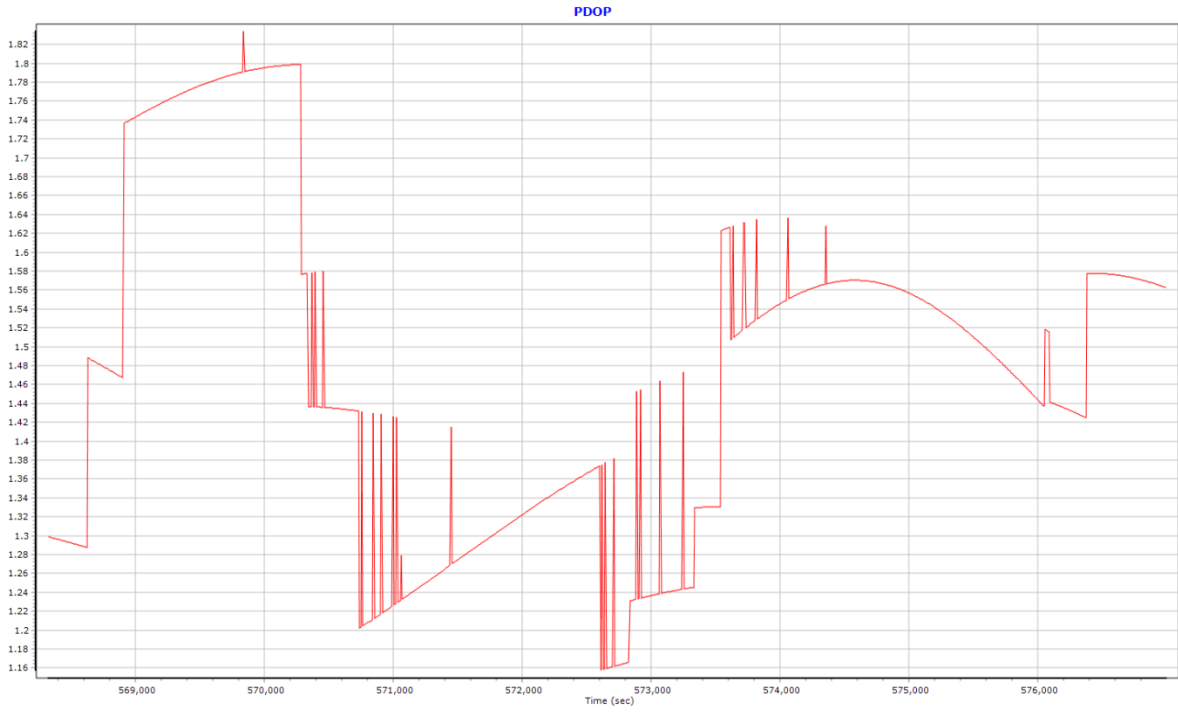
X:

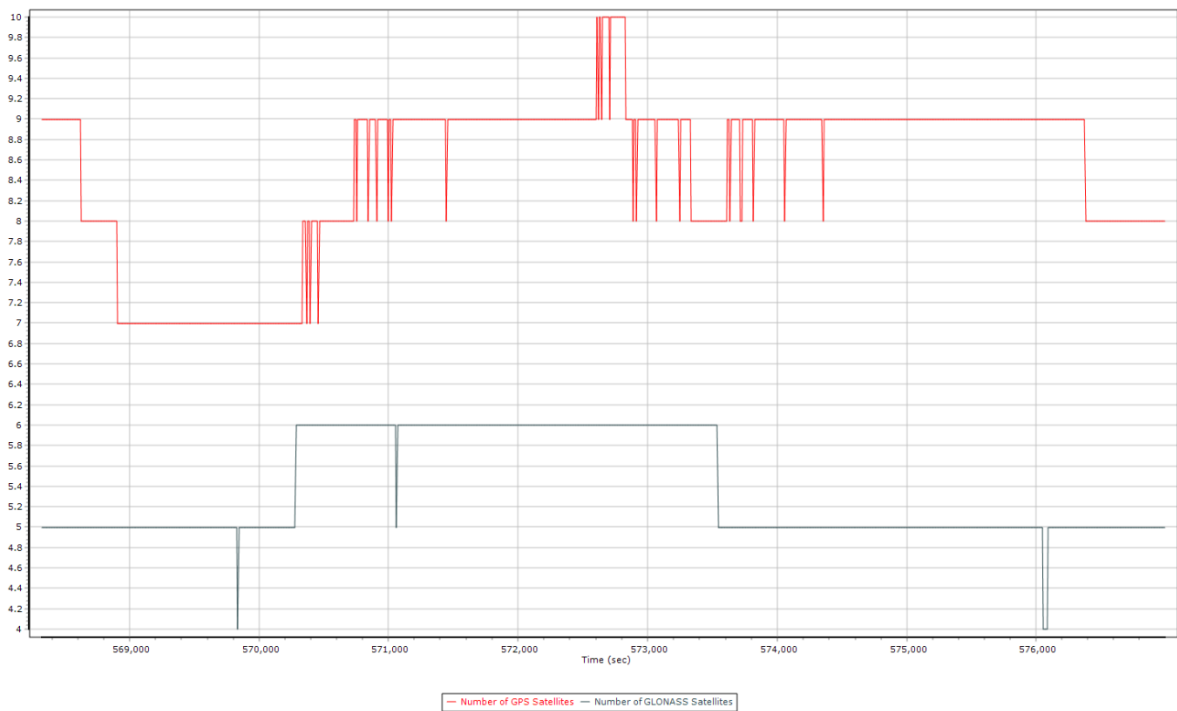
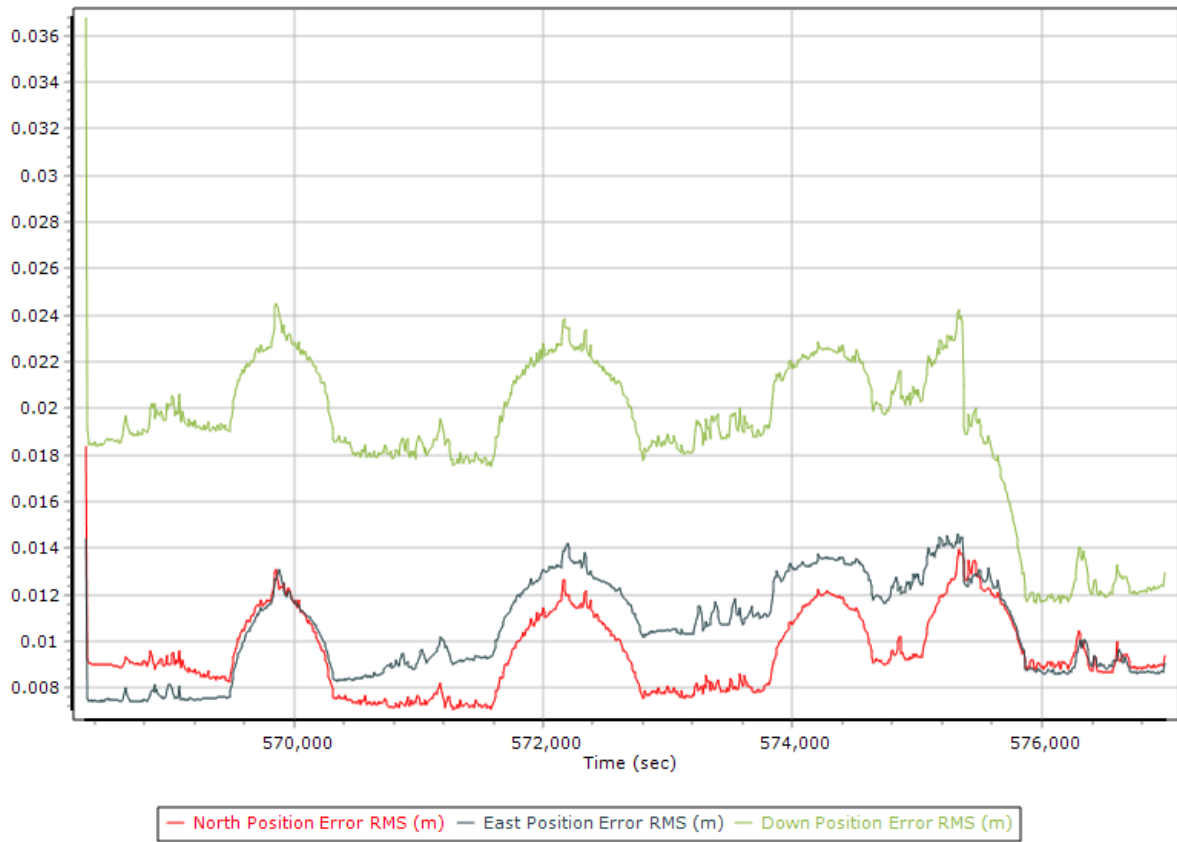
Y:

Z:

Standard Deviation

<3cm 10cm 50cm 1m 10m





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

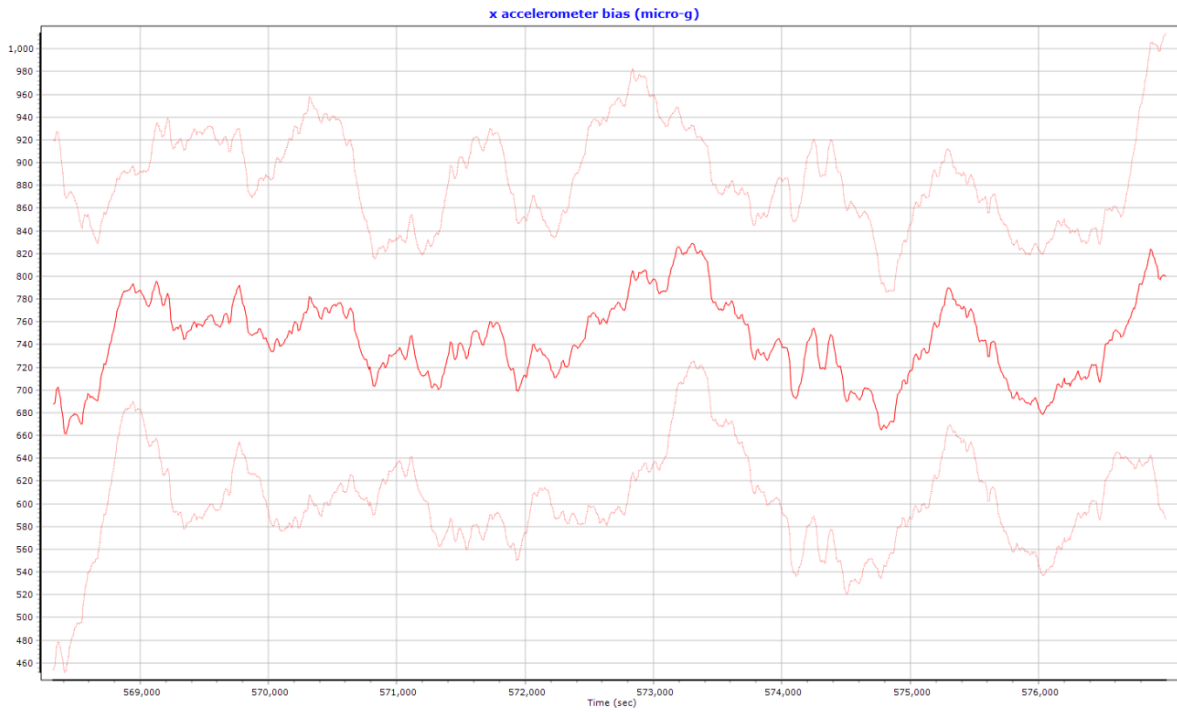
Start: 568321.641
End: 577001.025

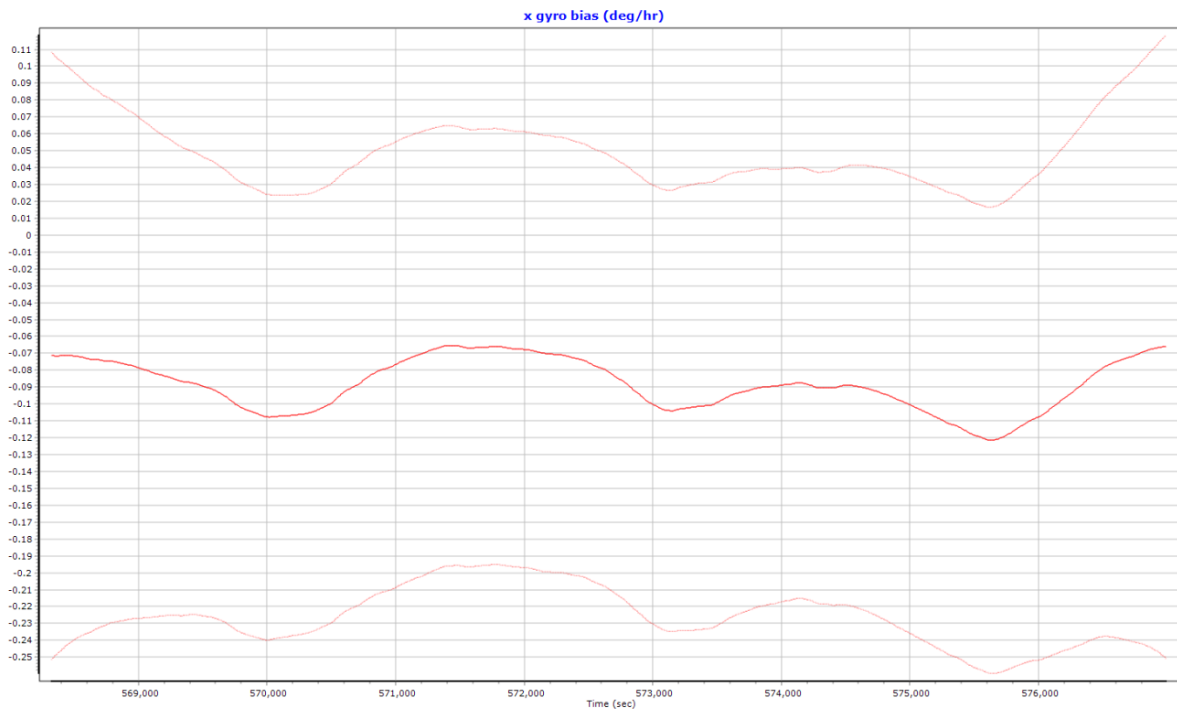
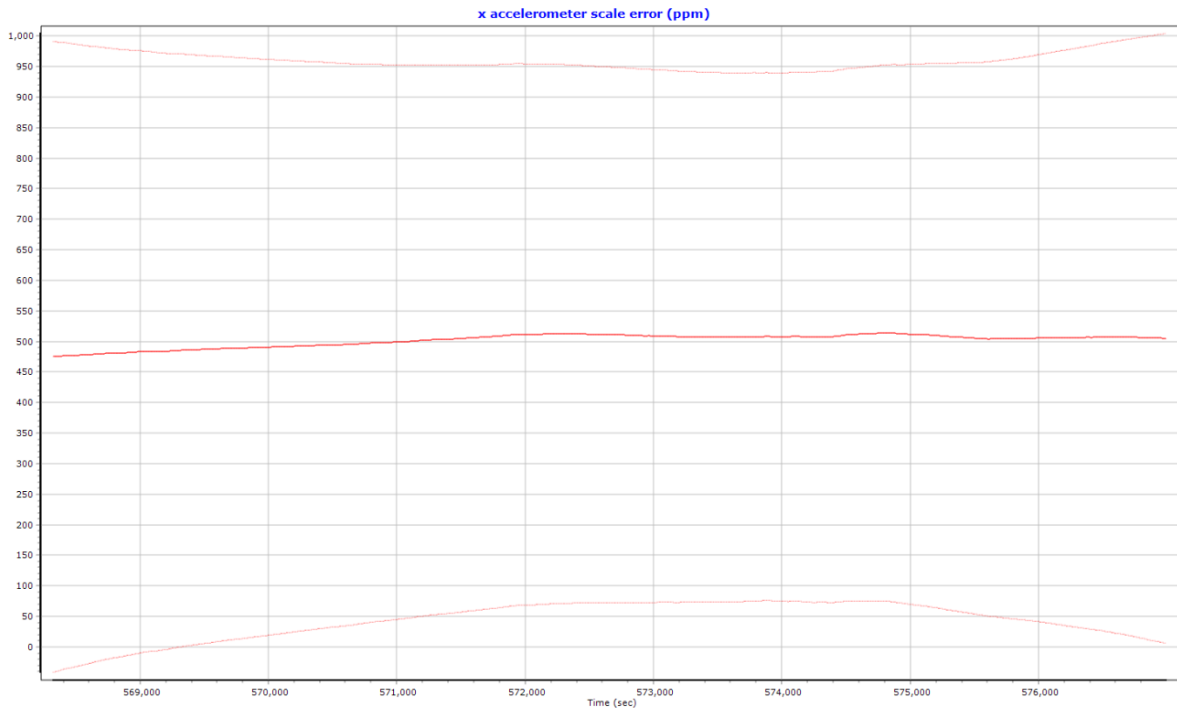
Entire time interval
 Seconds of start week

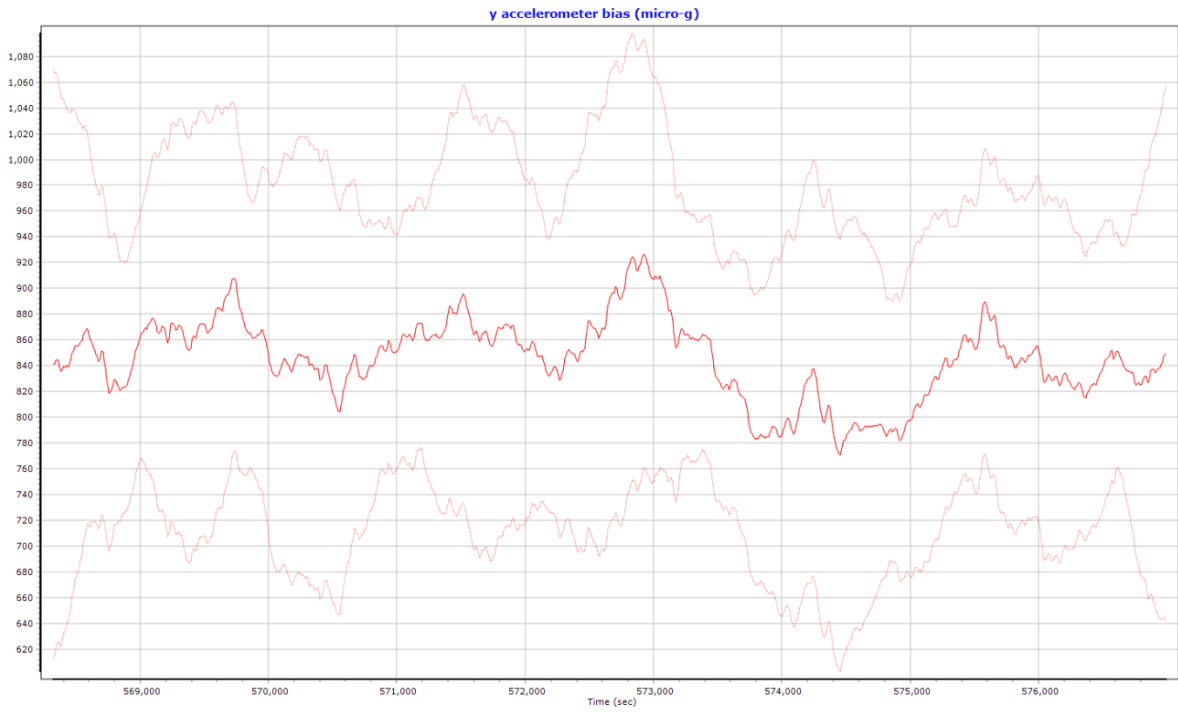
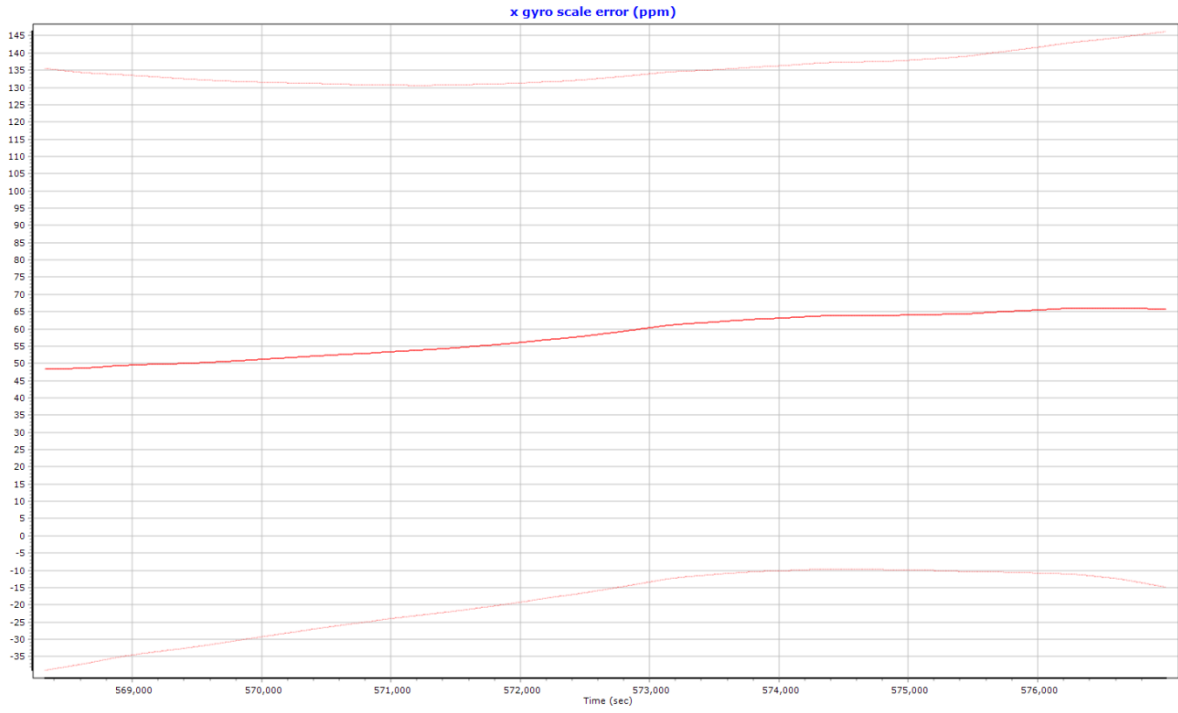
UTC Offset: 18.000

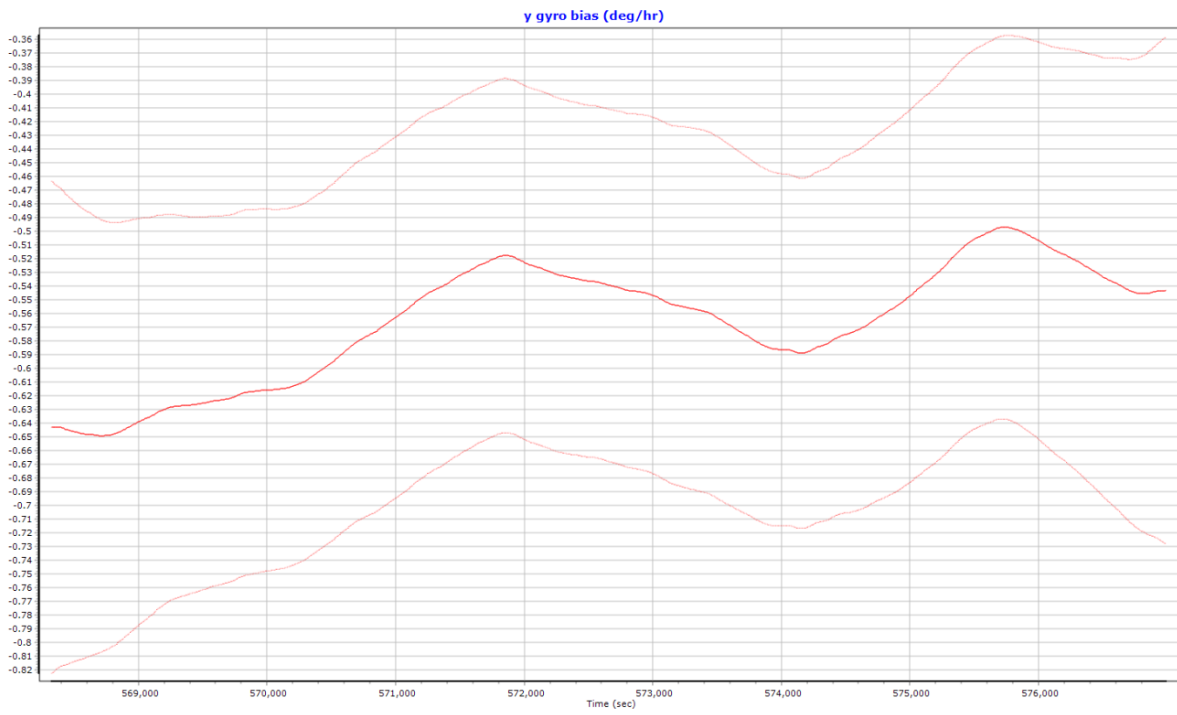
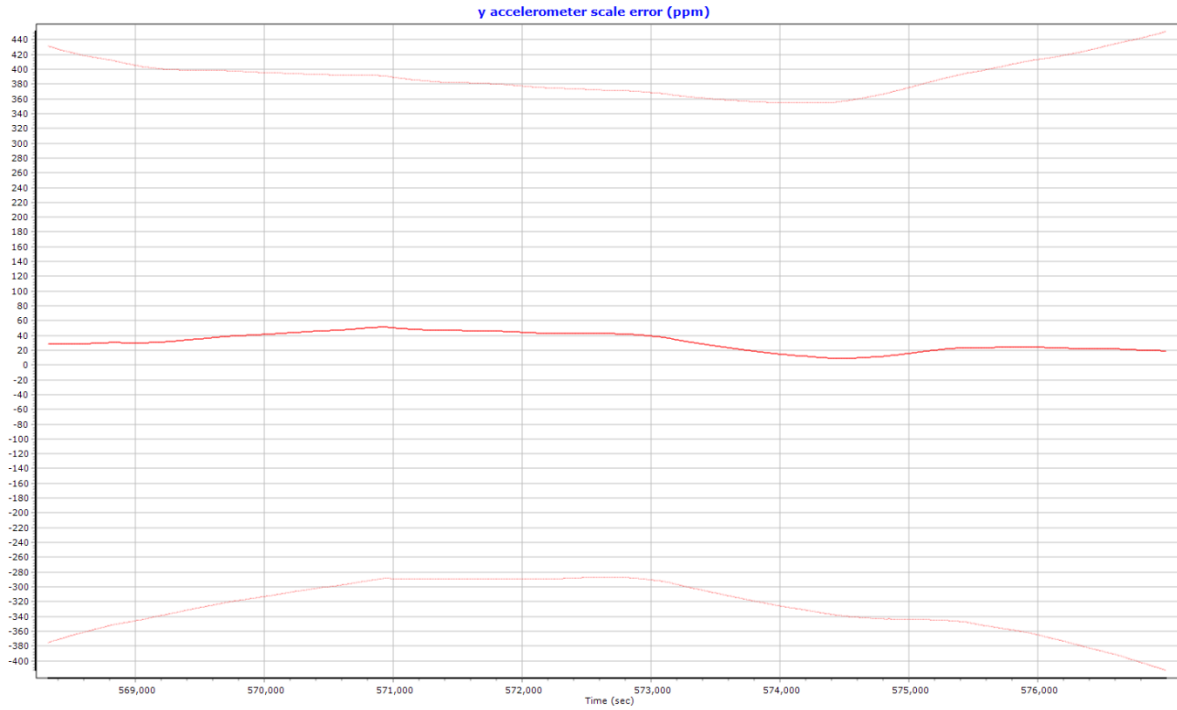
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

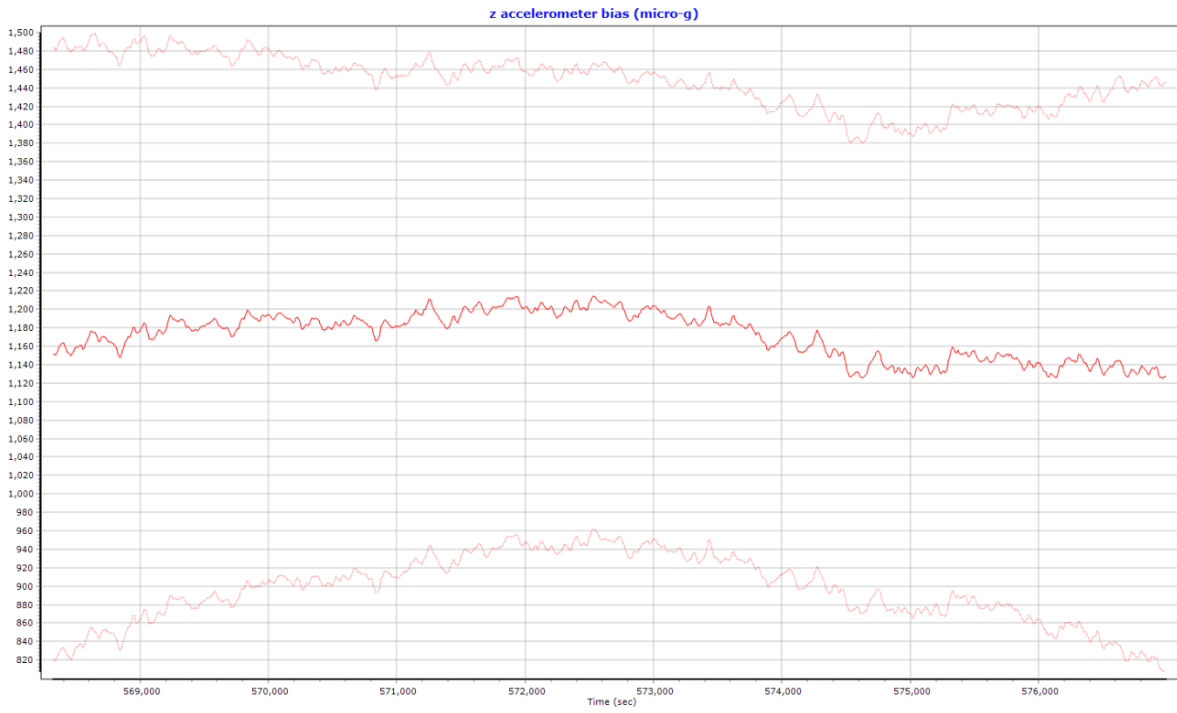
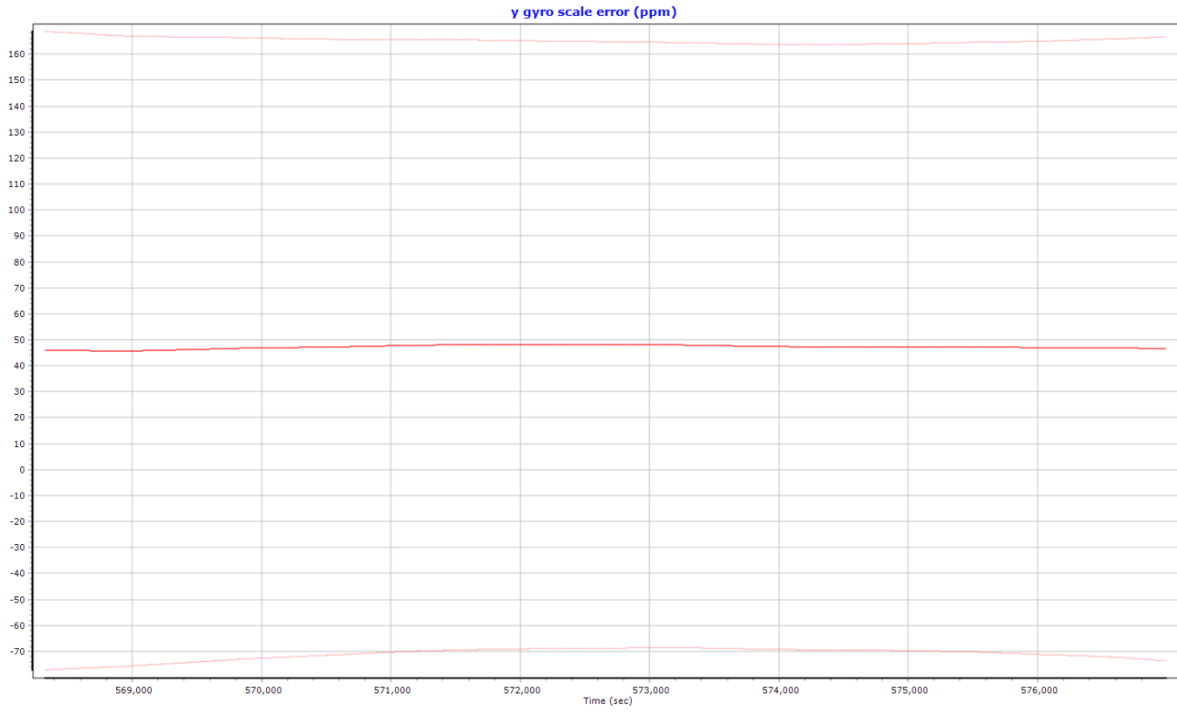
OK Cancel

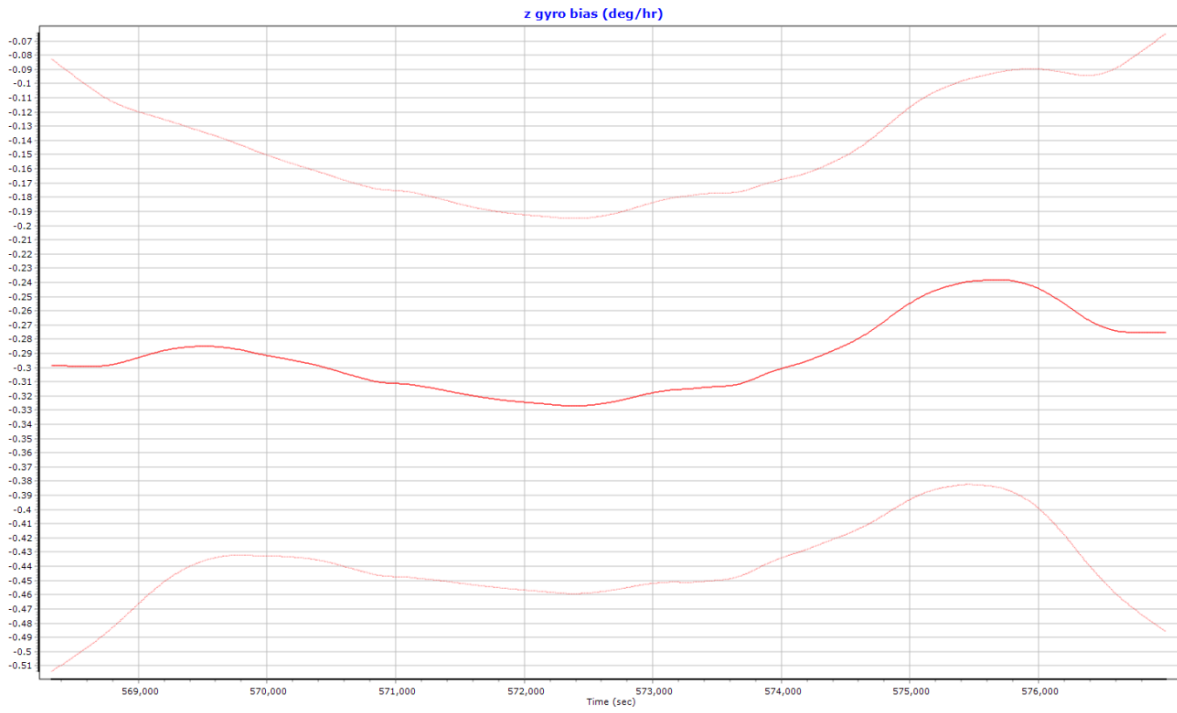
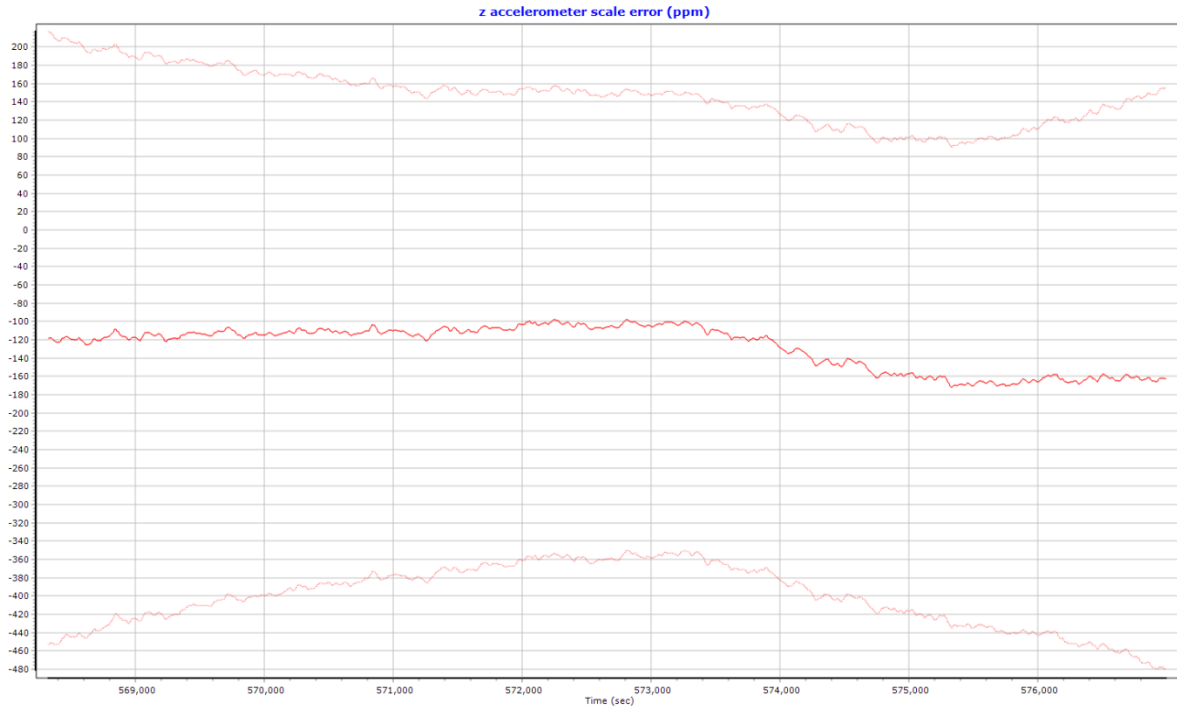


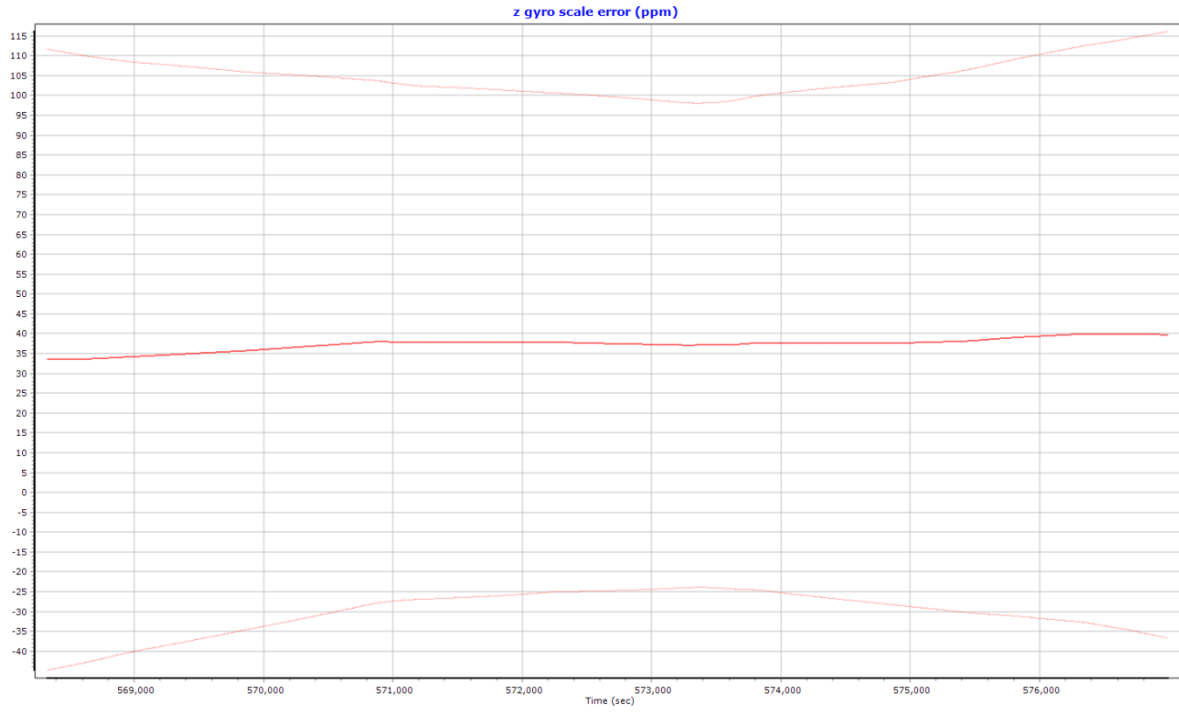




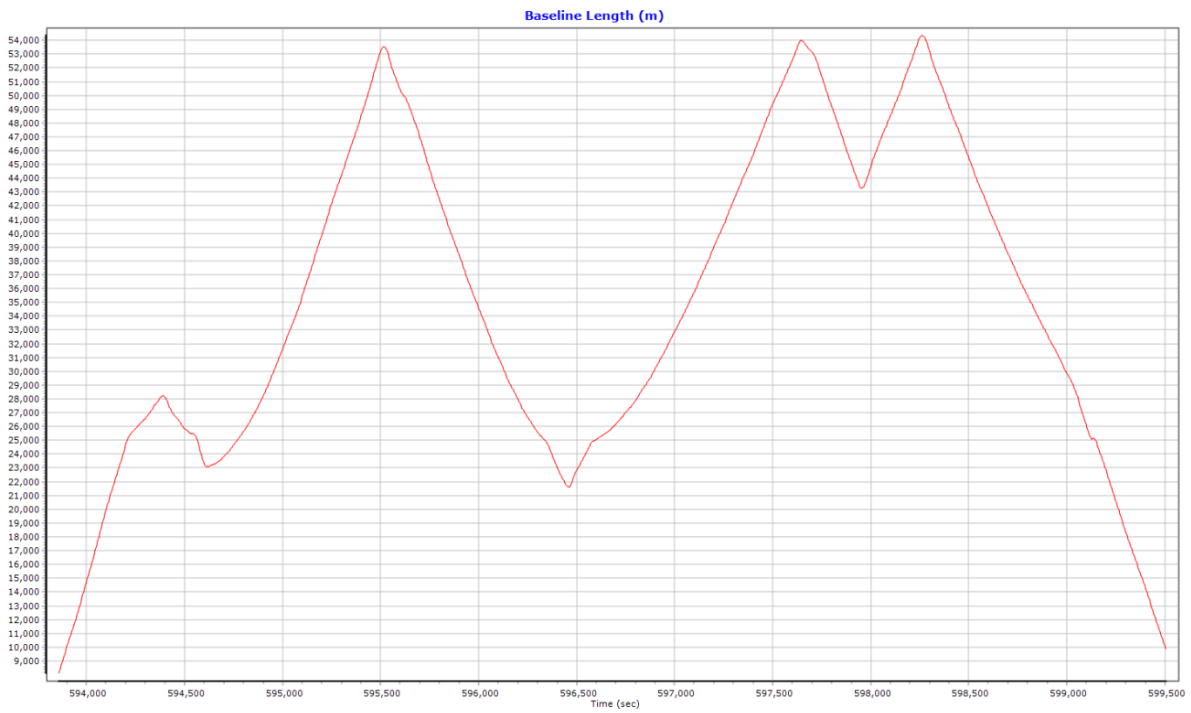
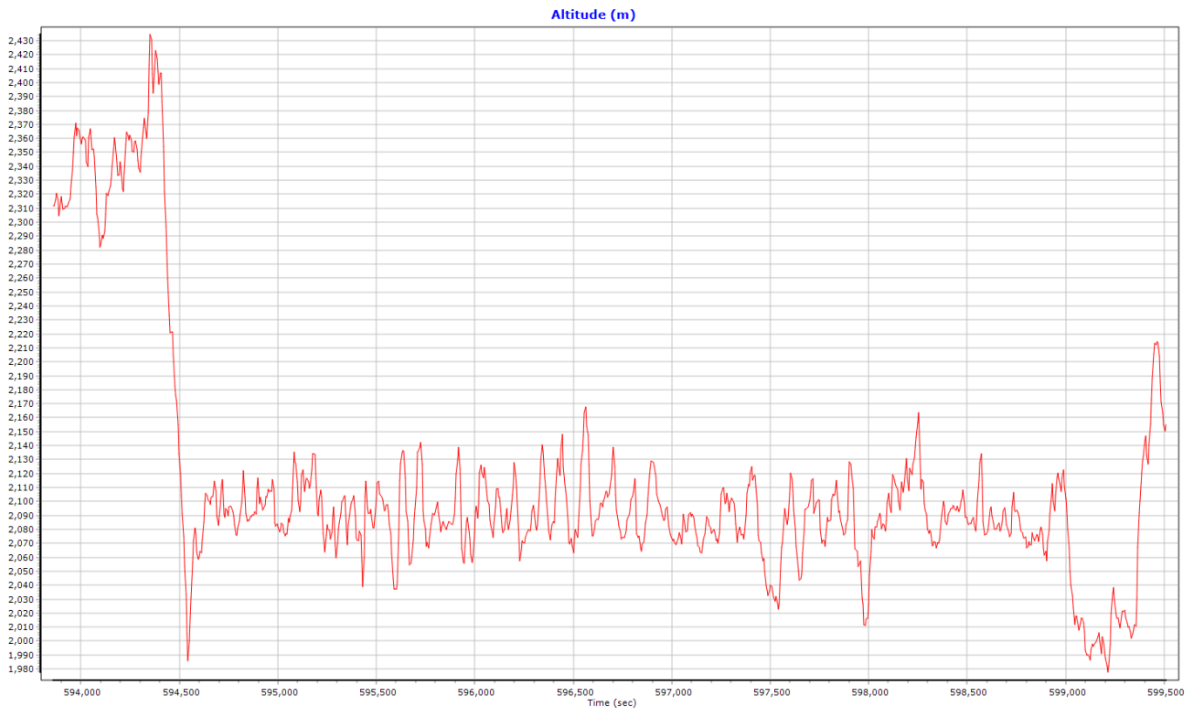


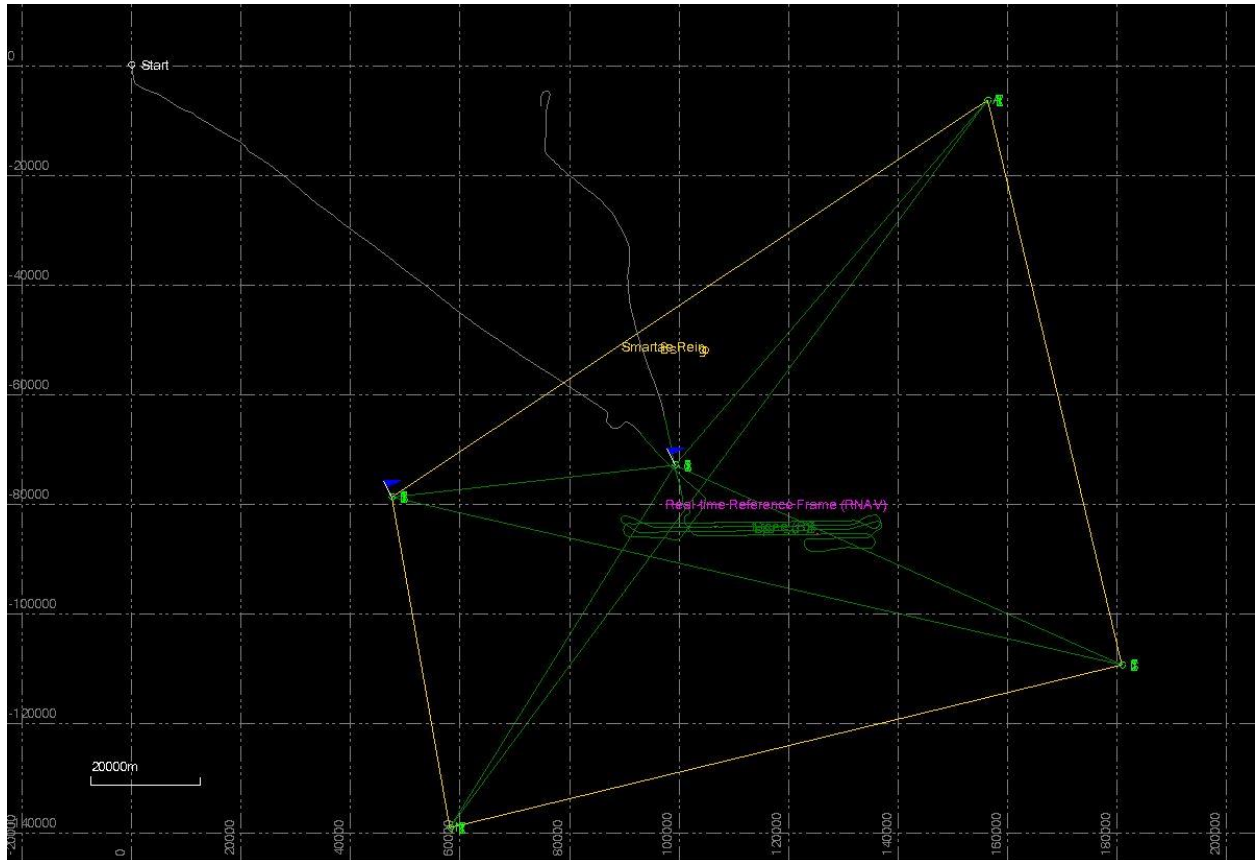


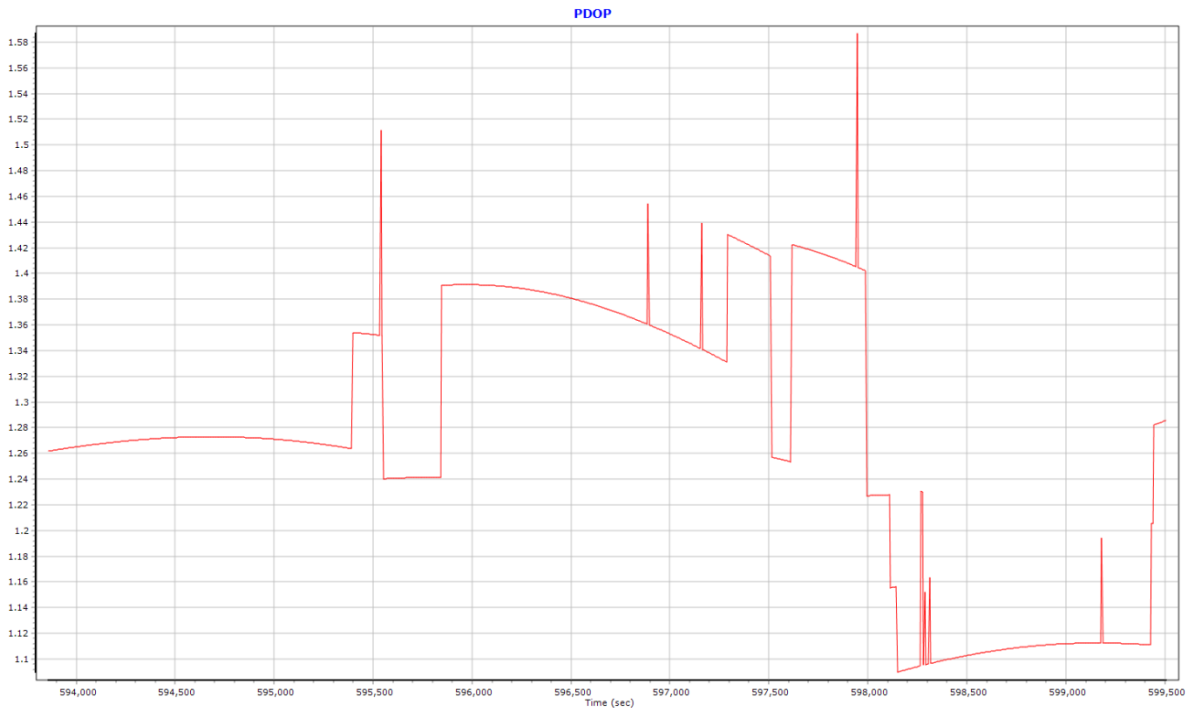
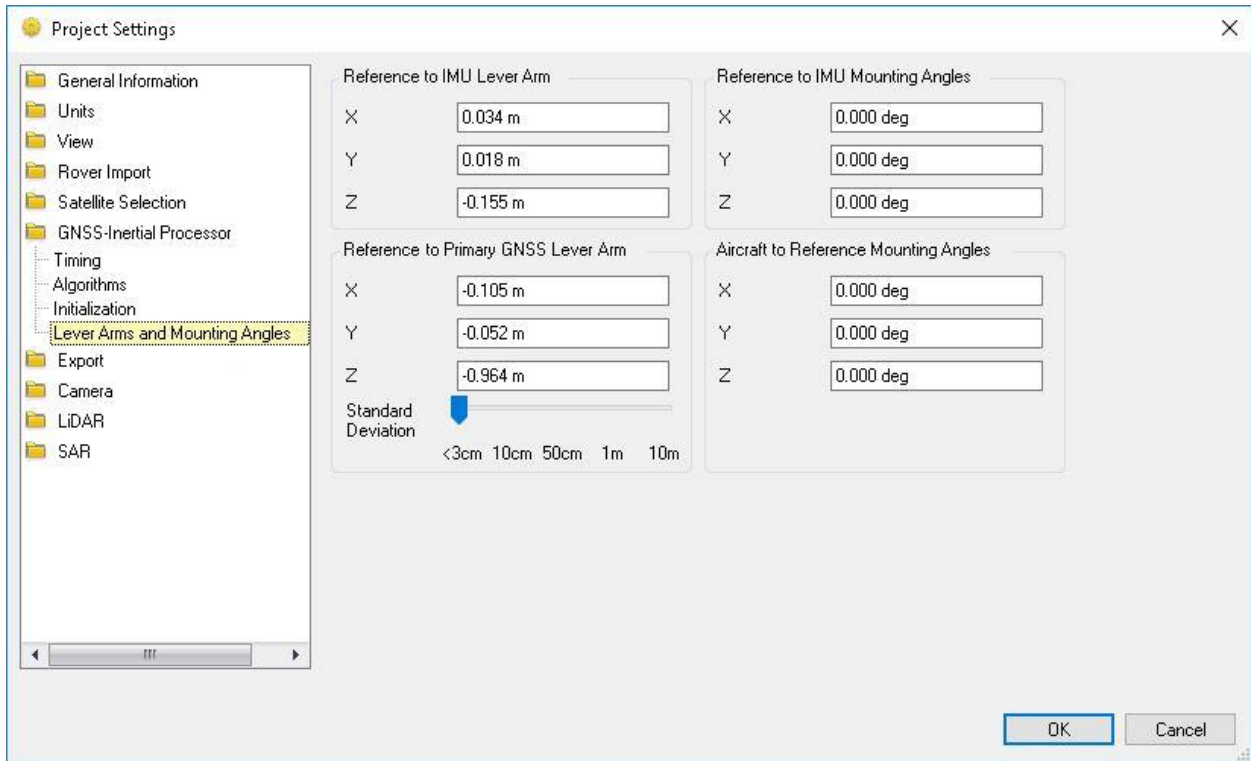


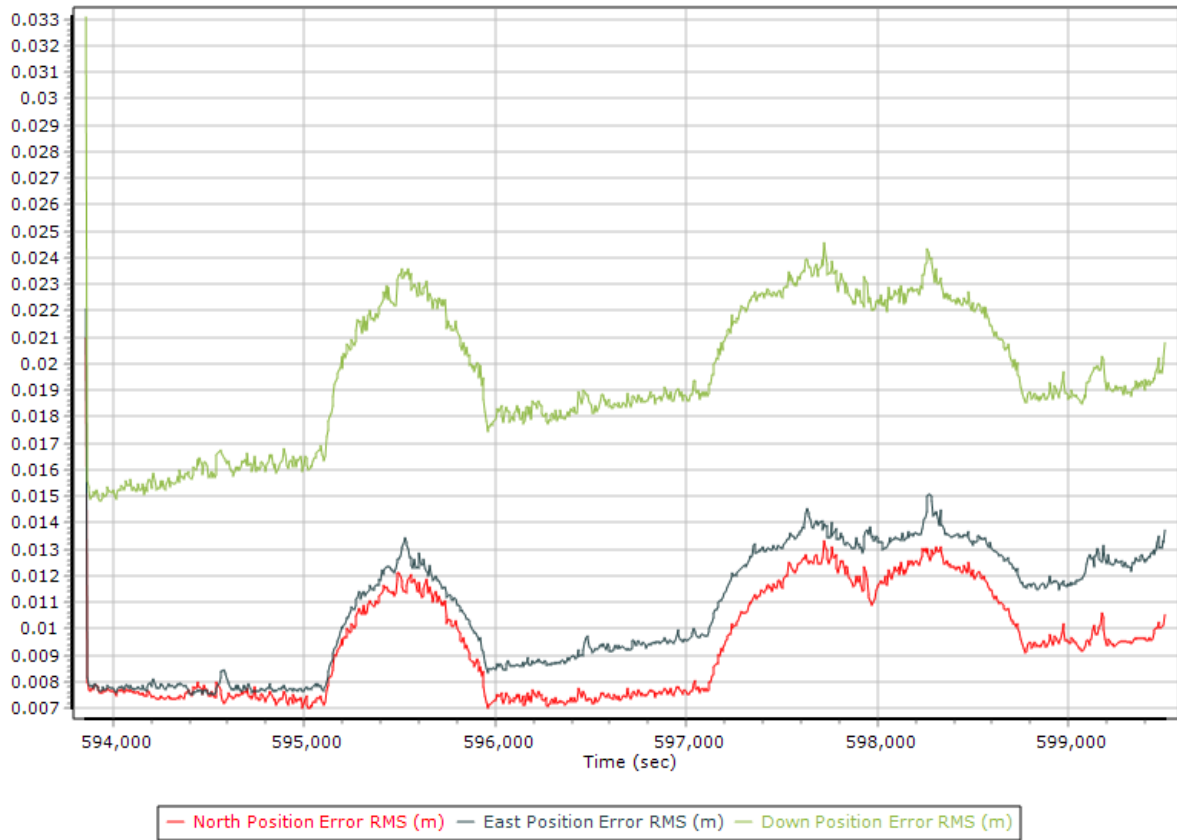


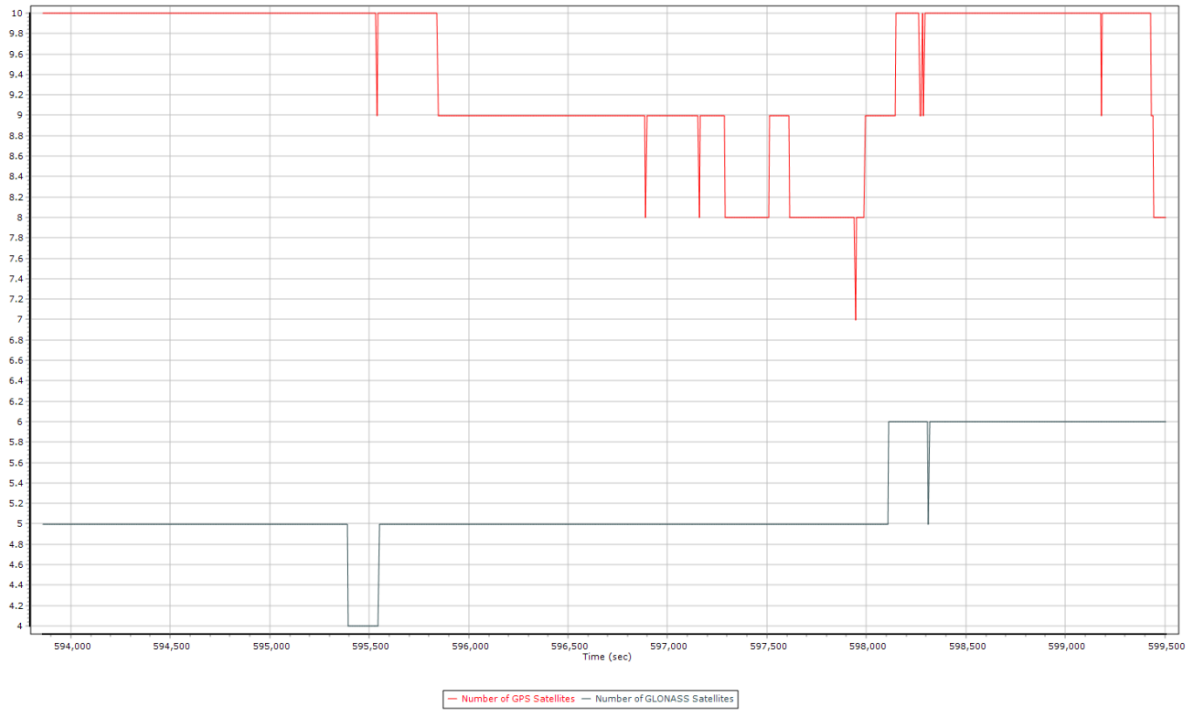
UNB18118B











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

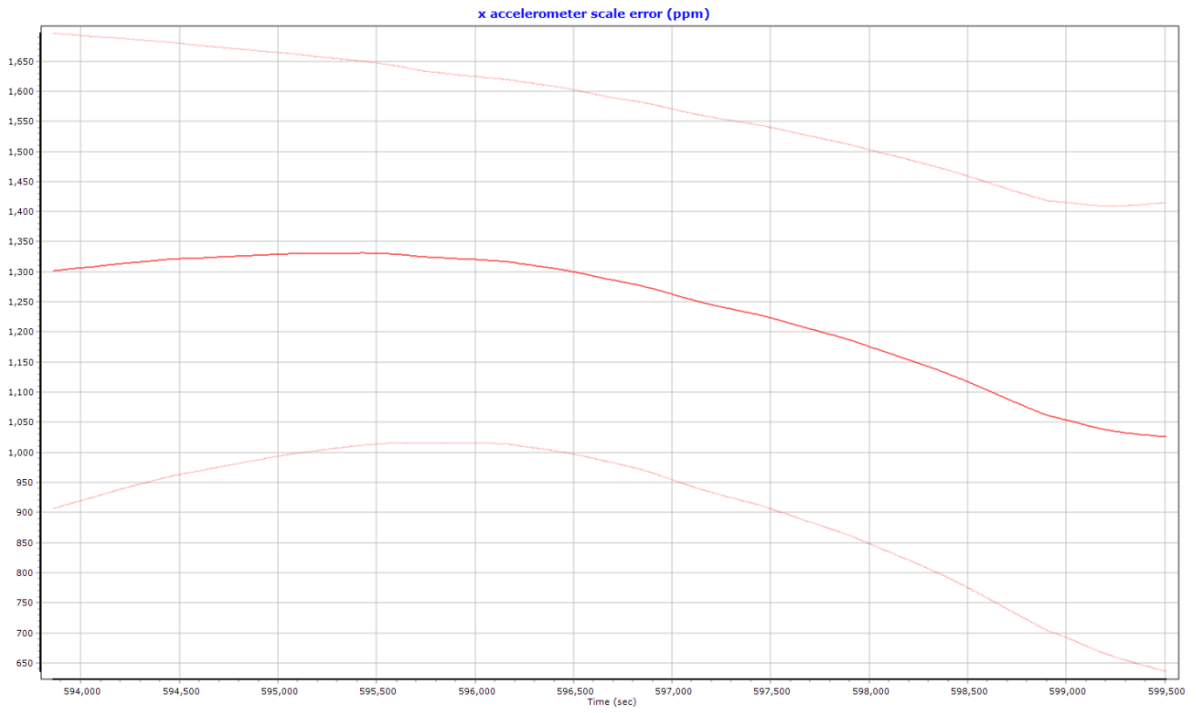
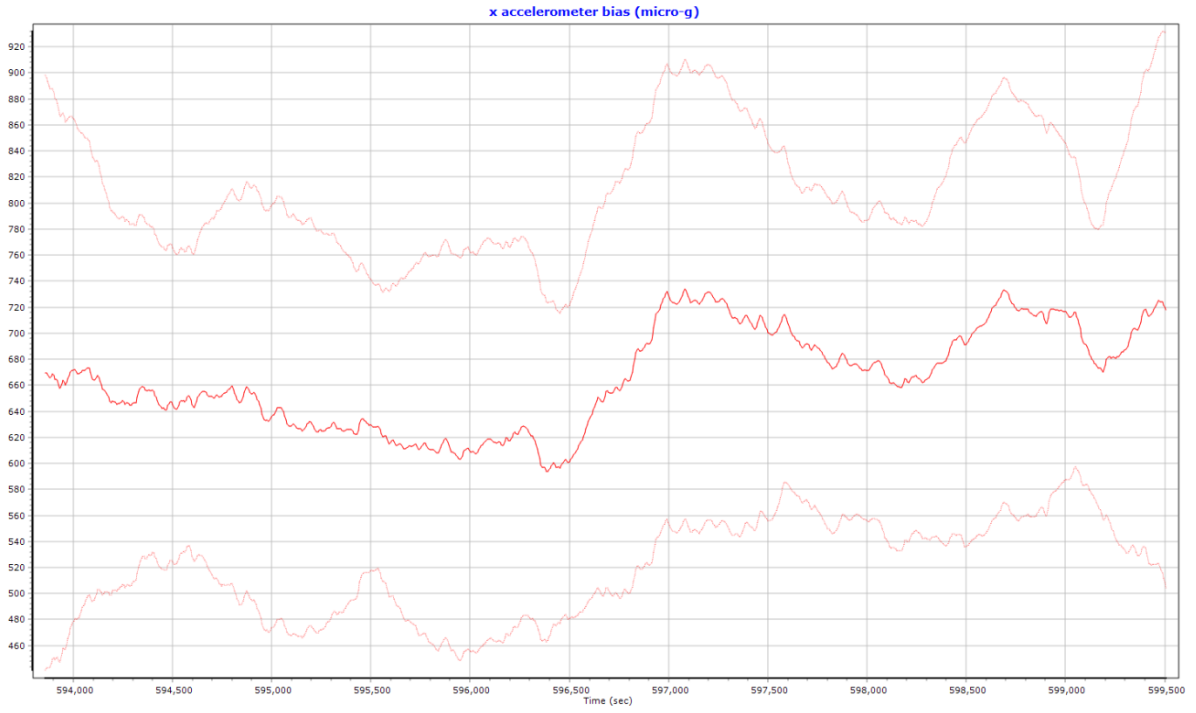
Start: 593856.857
End: 599515.074

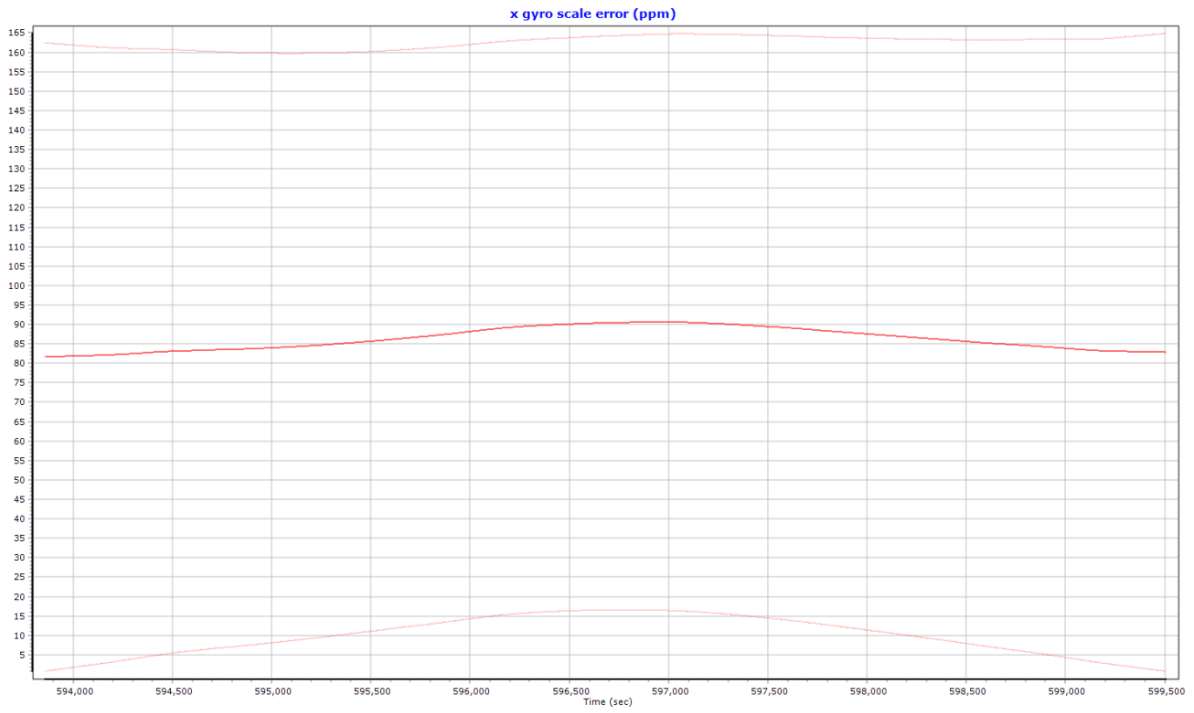
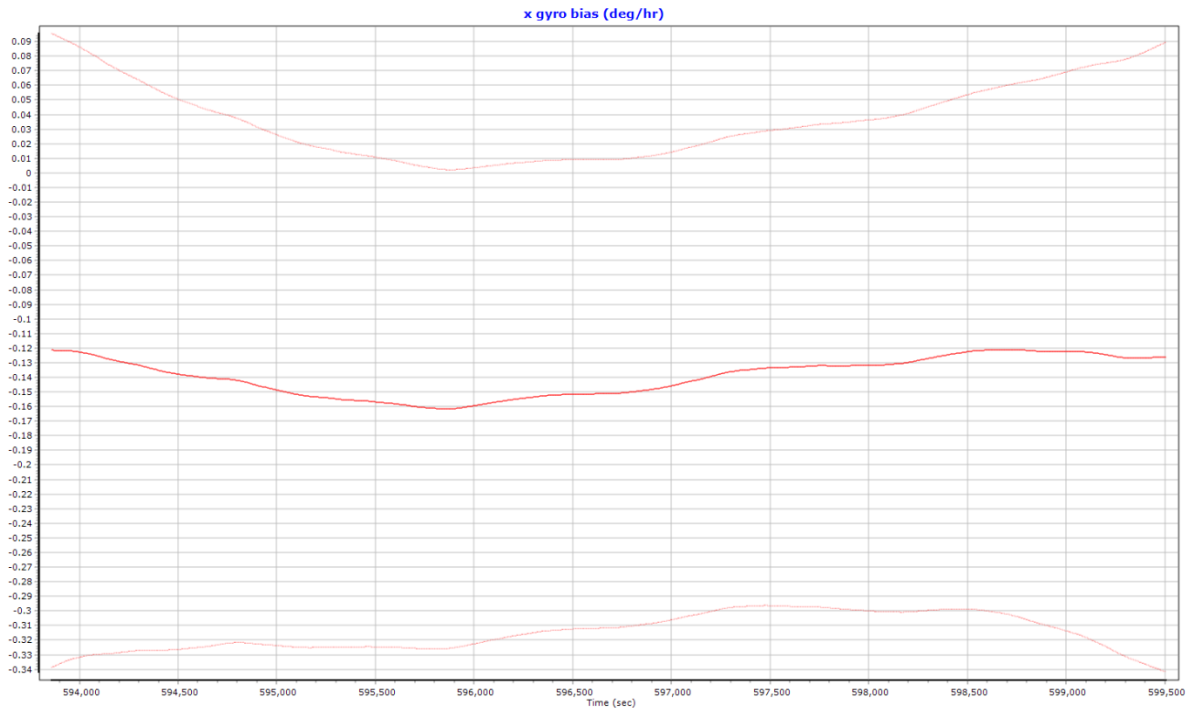
Entire time interval
 Seconds of start week

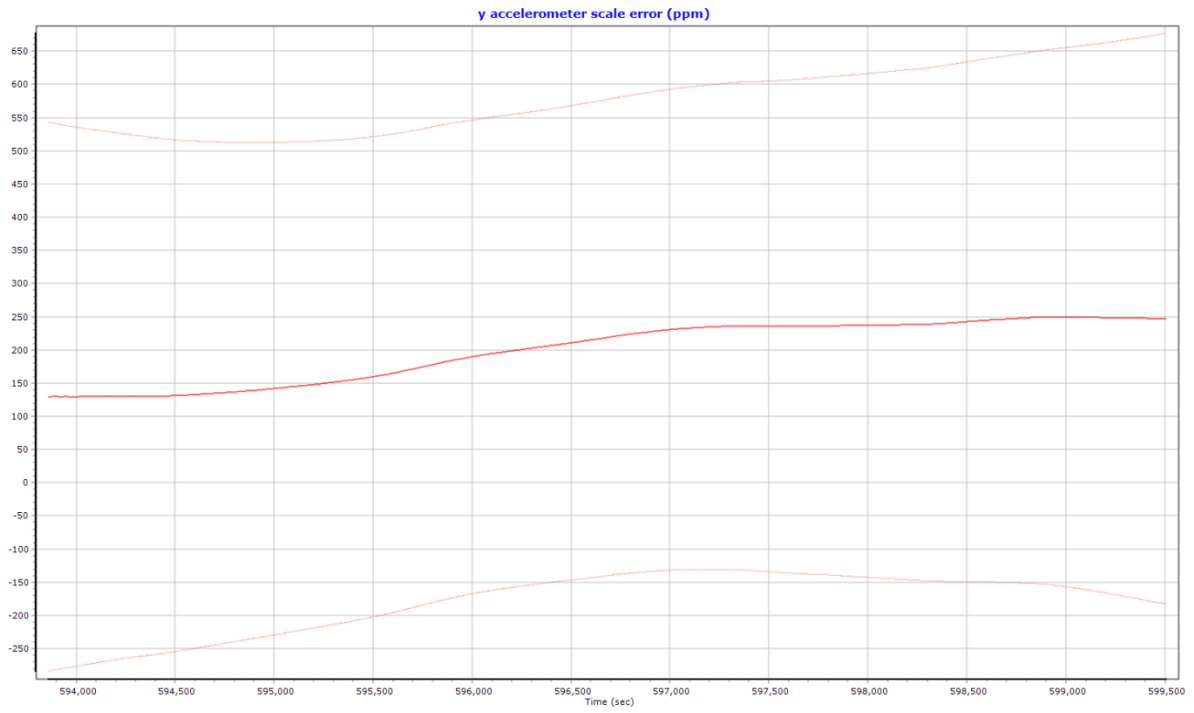
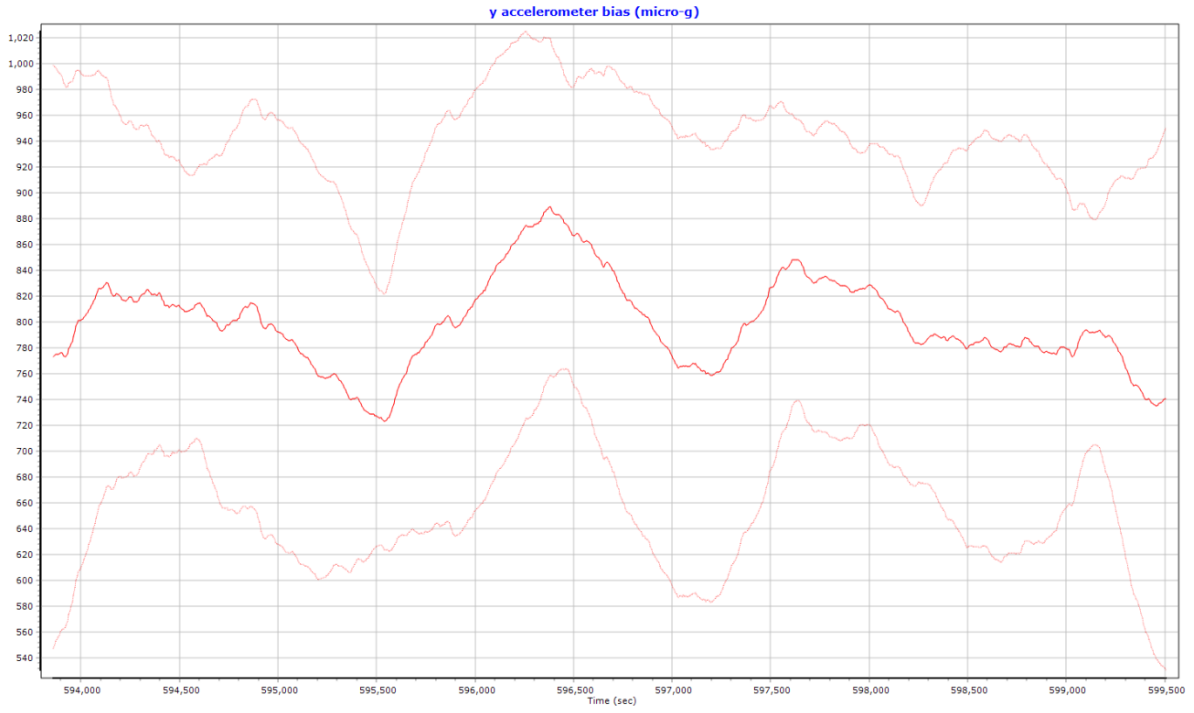
UTC Offset: 18.000

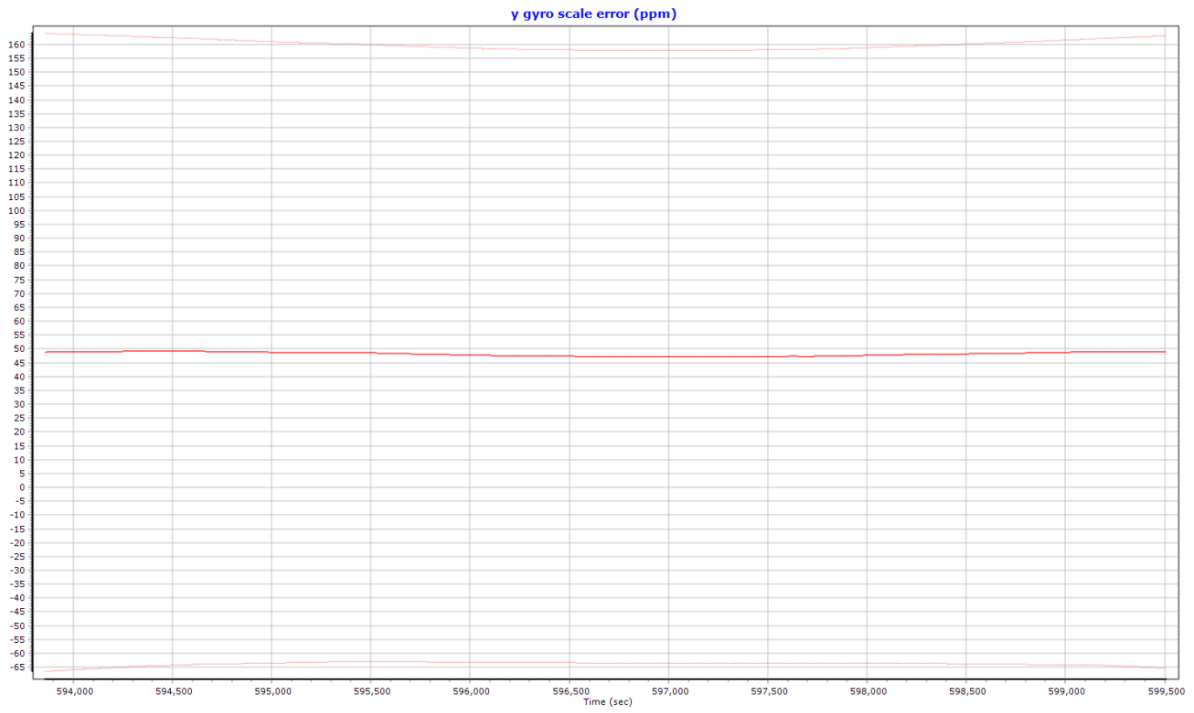
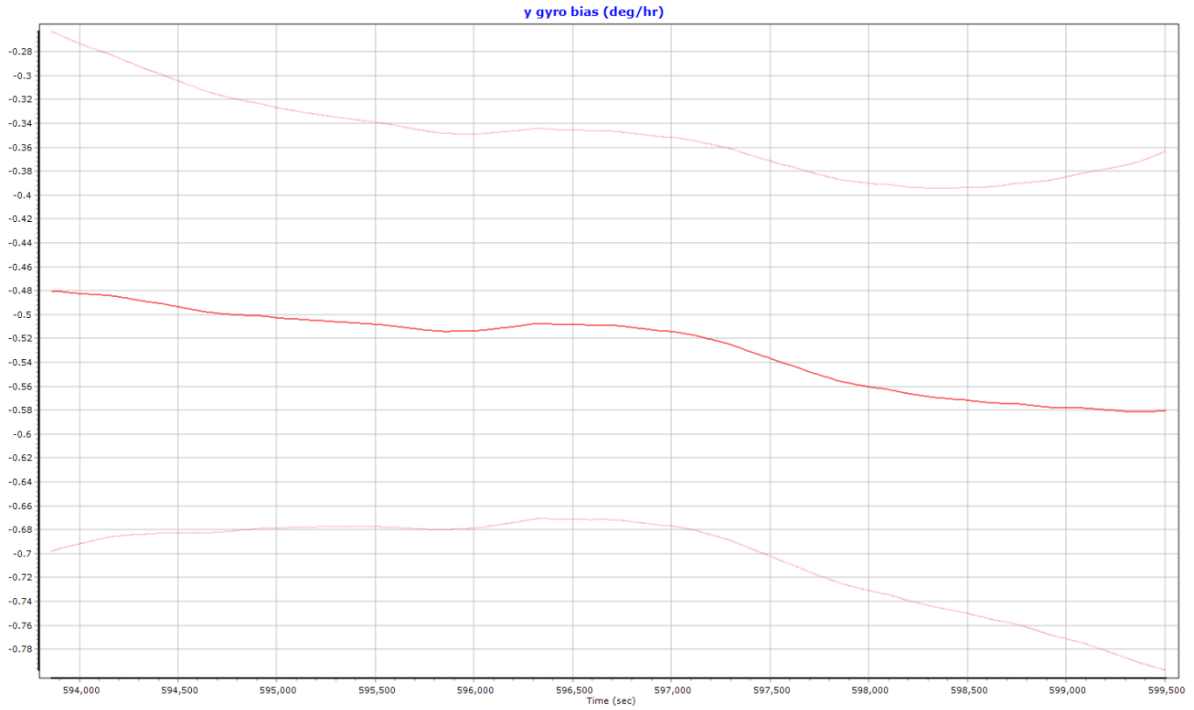
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

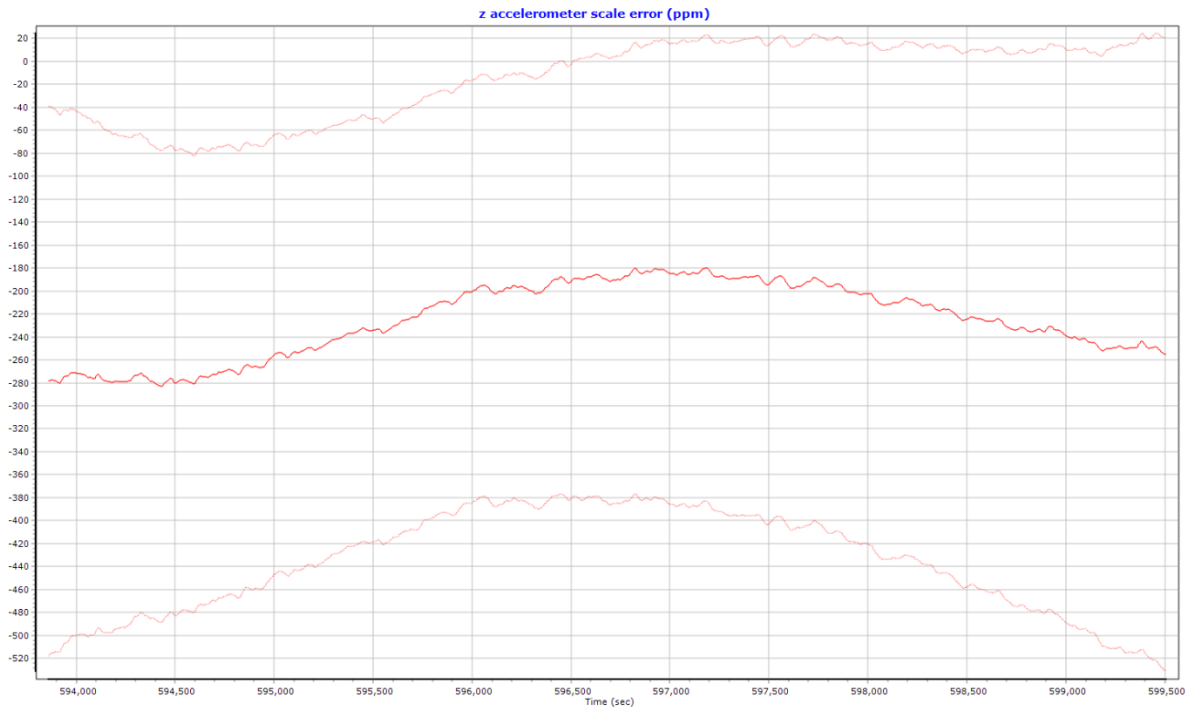
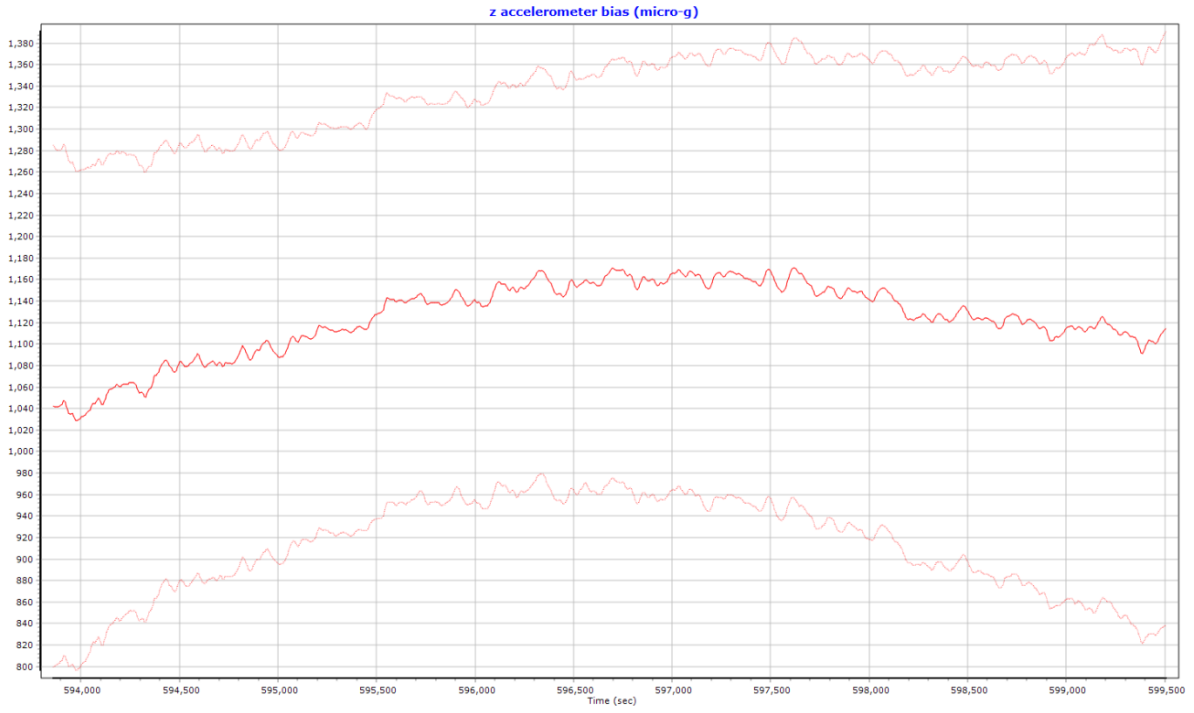
OK Cancel

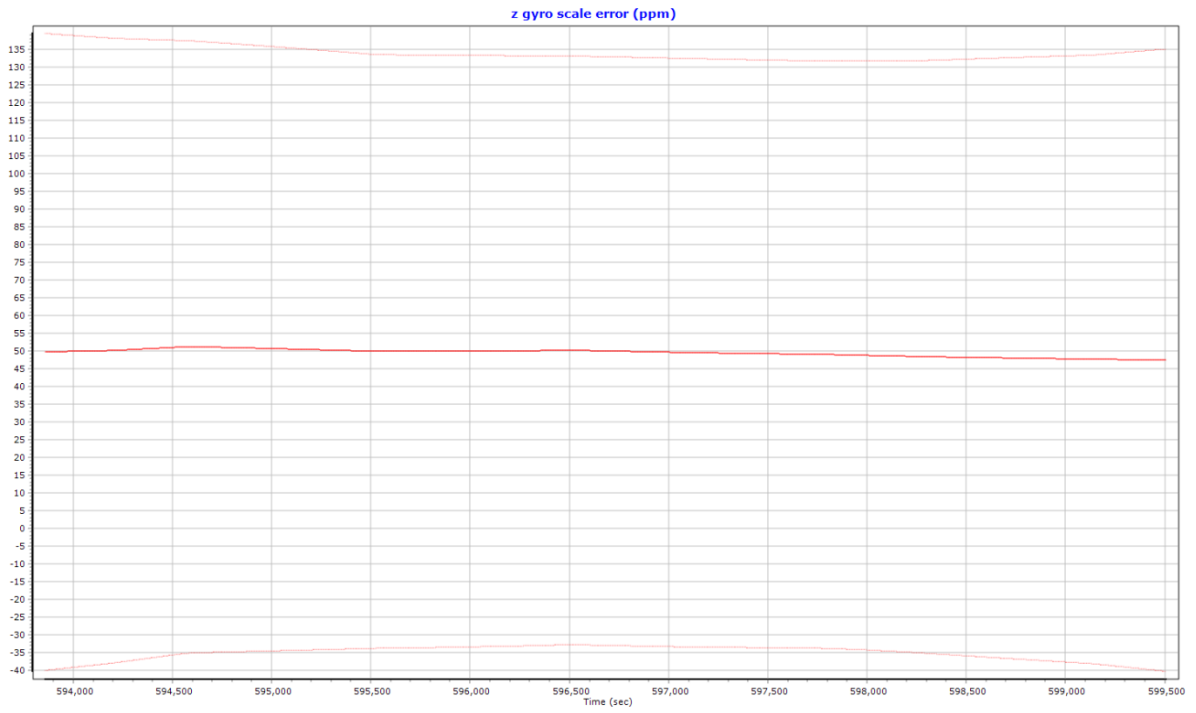
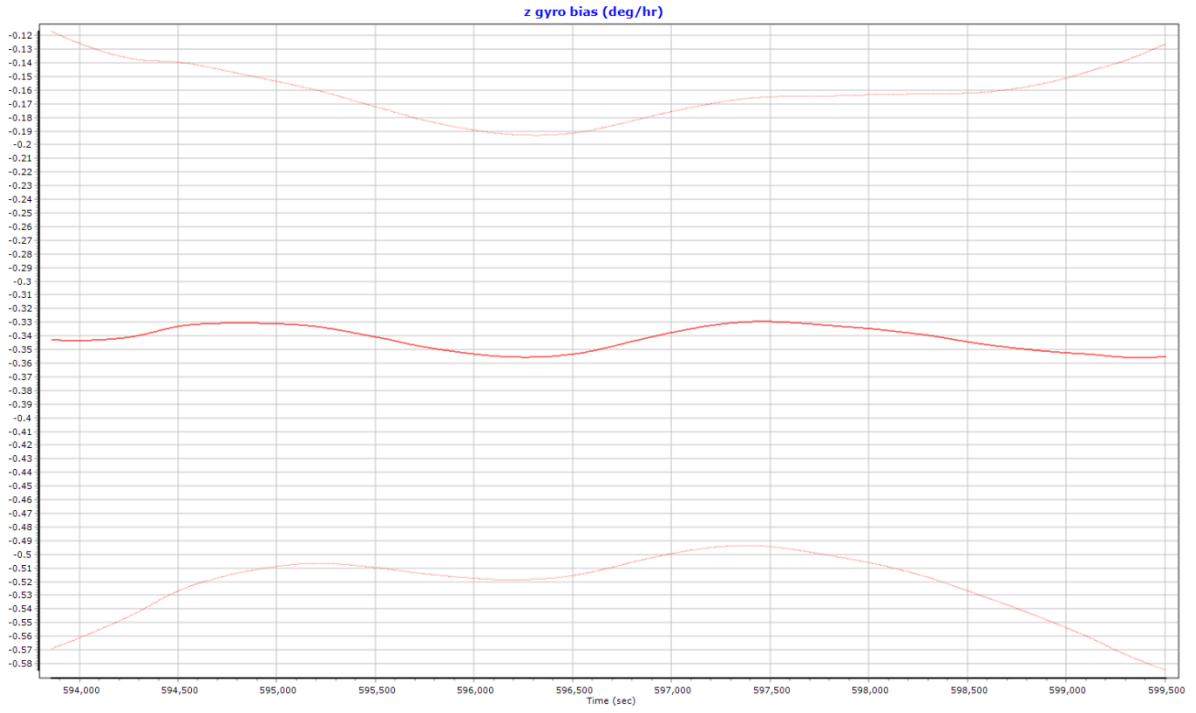




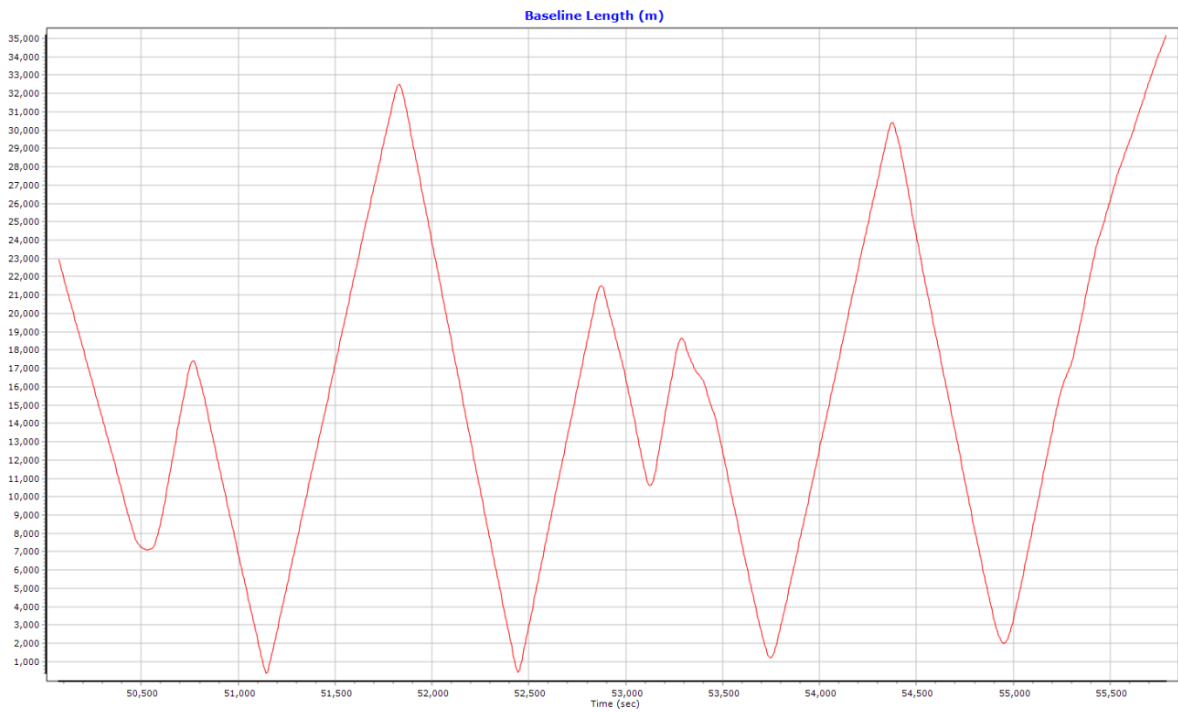
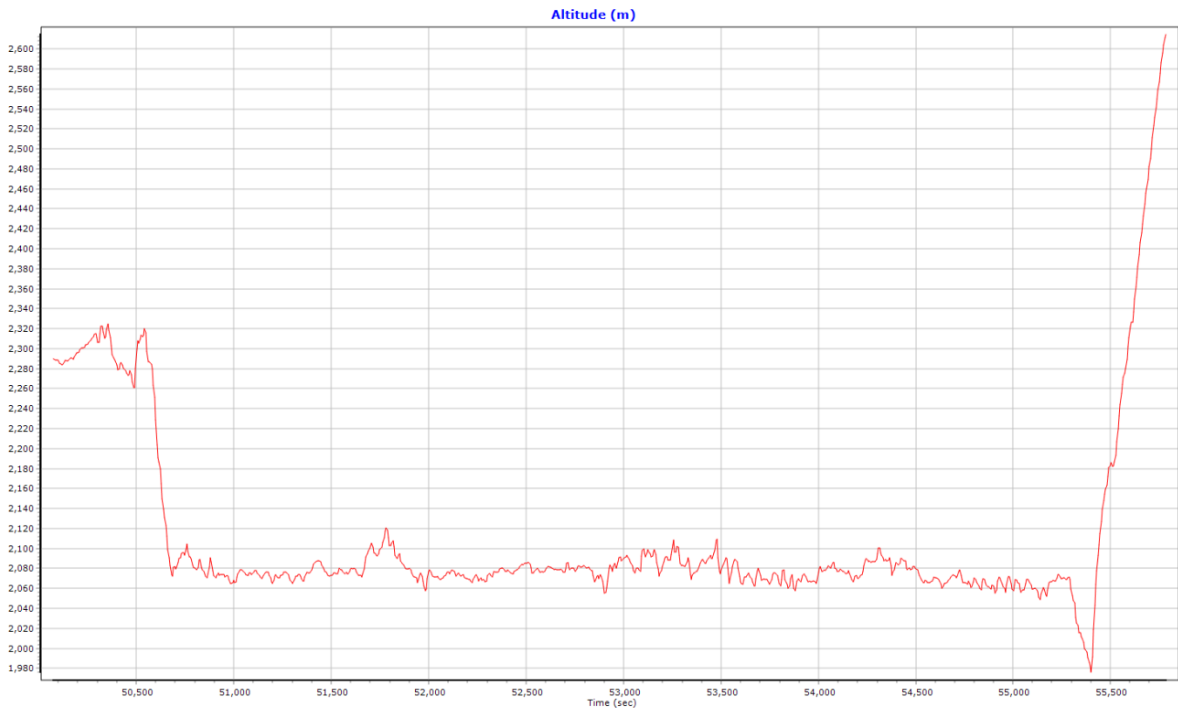


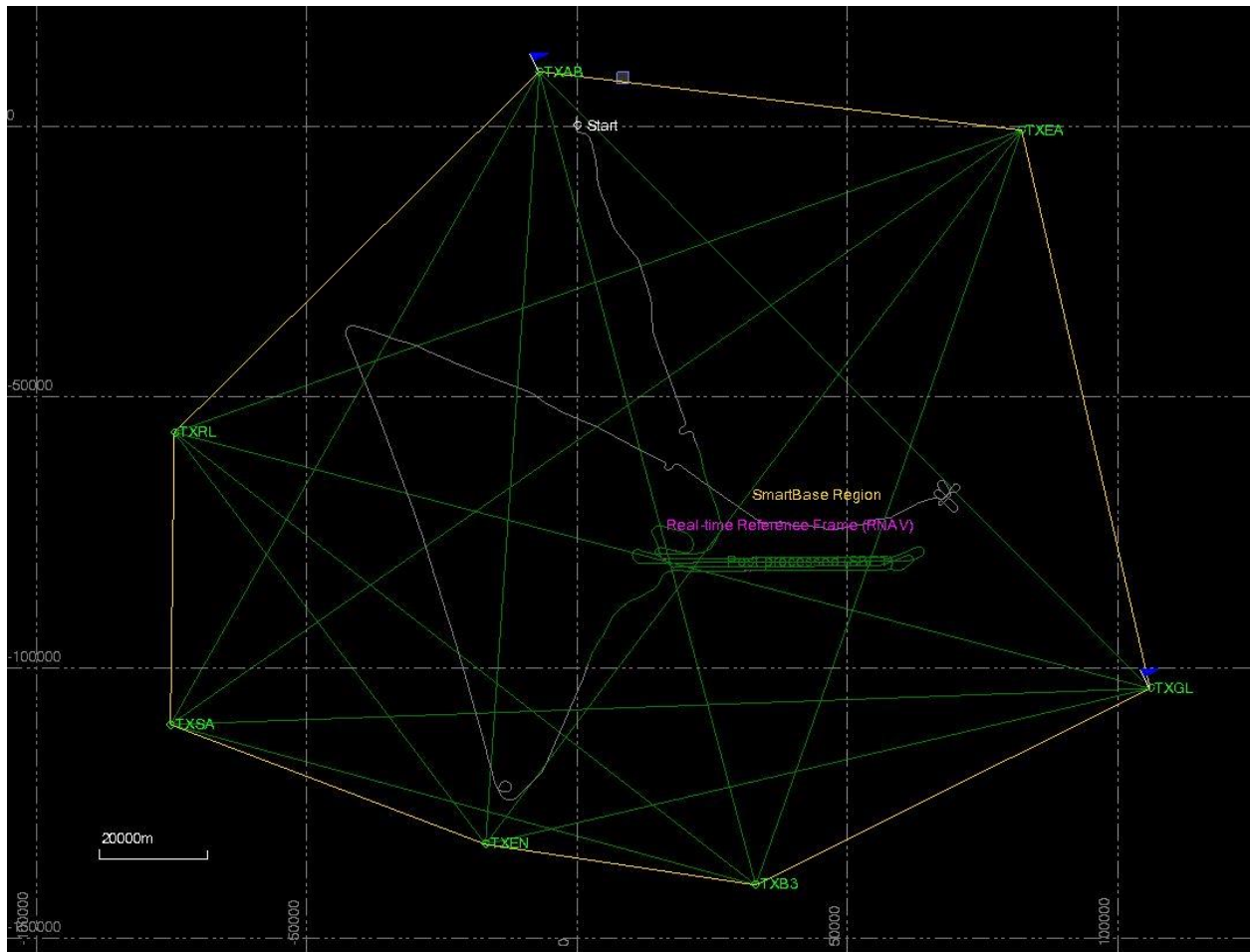






UNB18119A





Project Settings

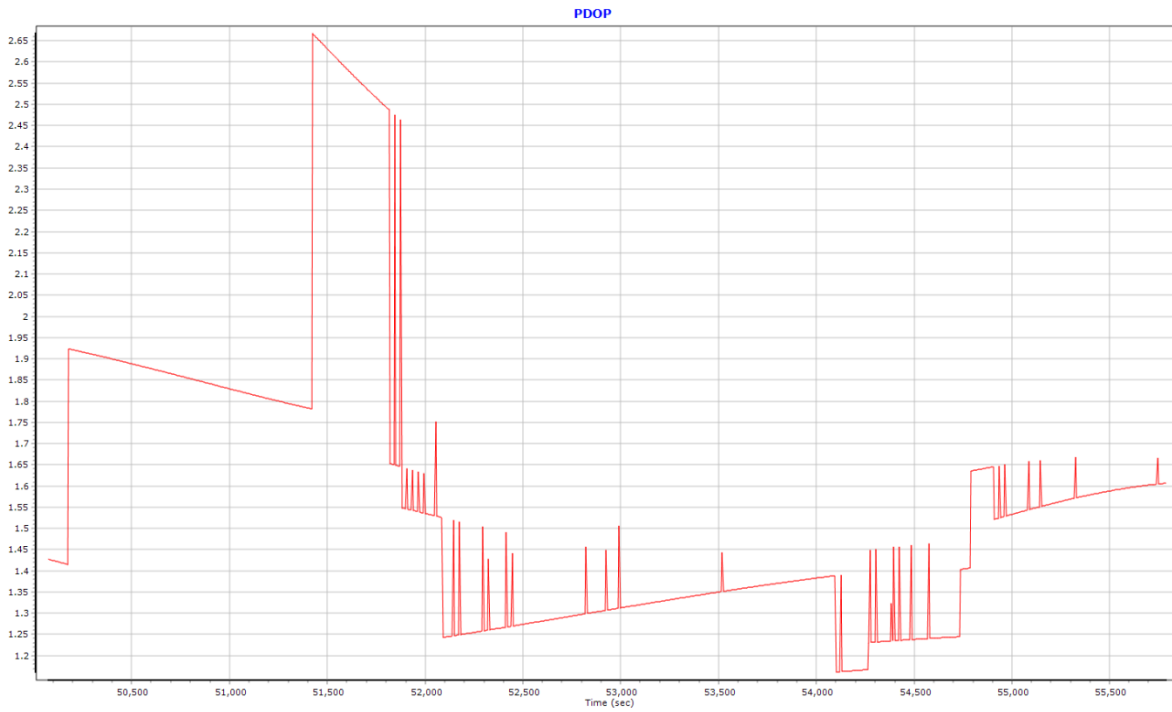
- General Information
- Units
- View
- Rover Import
- Satellite Selection
- GNSS-Inertial Processor
 - Timing
 - Algorithms
 - Initialization
 - Lever Arms and Mounting Angles**
- Export
- Camera
- LiDAR
- SAR

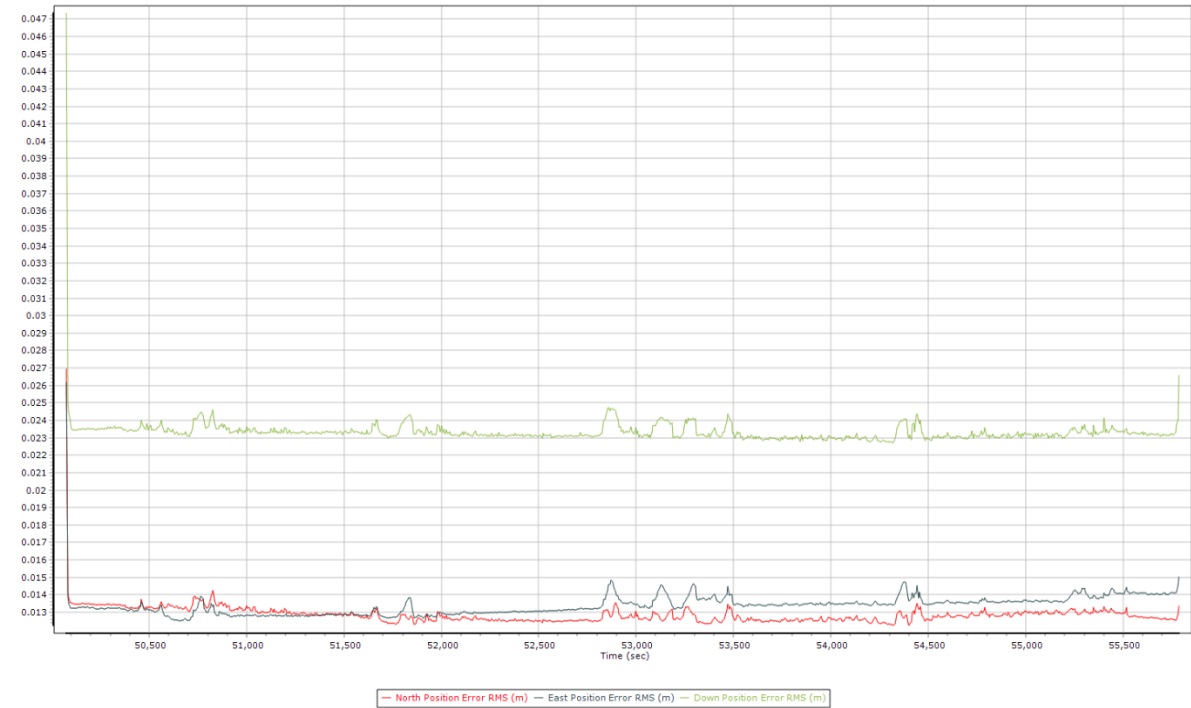
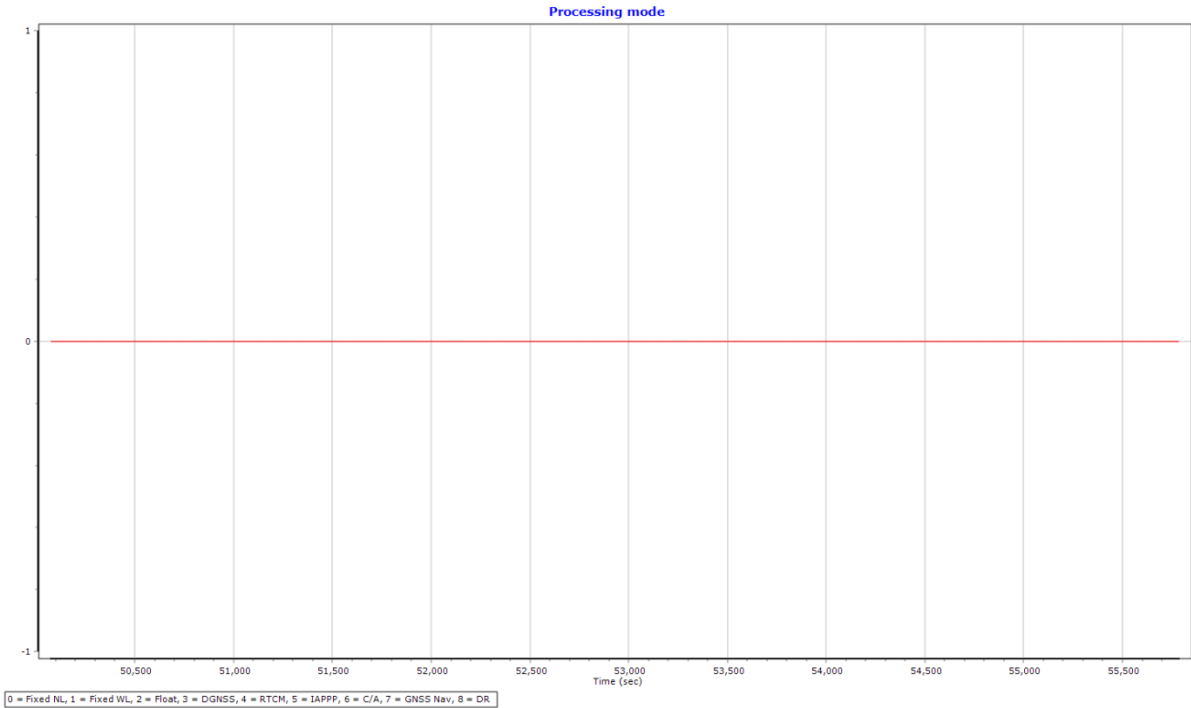
Reference to IMU Lever Arm	Reference to IMU Mounting Angles
X: 0.034 m	X: 0.000 deg
Y: 0.018 m	Y: 0.000 deg
Z: -0.155 m	Z: 0.000 deg

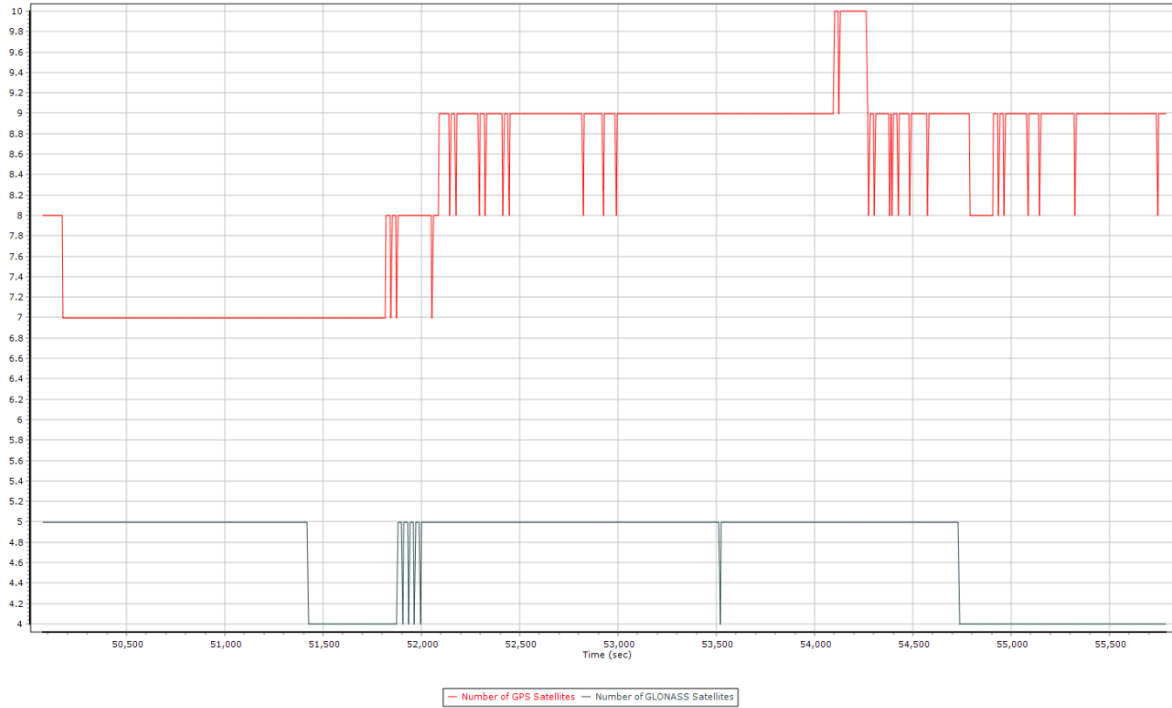
Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.105 m	X: 0.000 deg
Y: -0.052 m	Y: 0.000 deg
Z: -0.964 m	Z: 0.000 deg

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: 47555.000

End: 62284.000

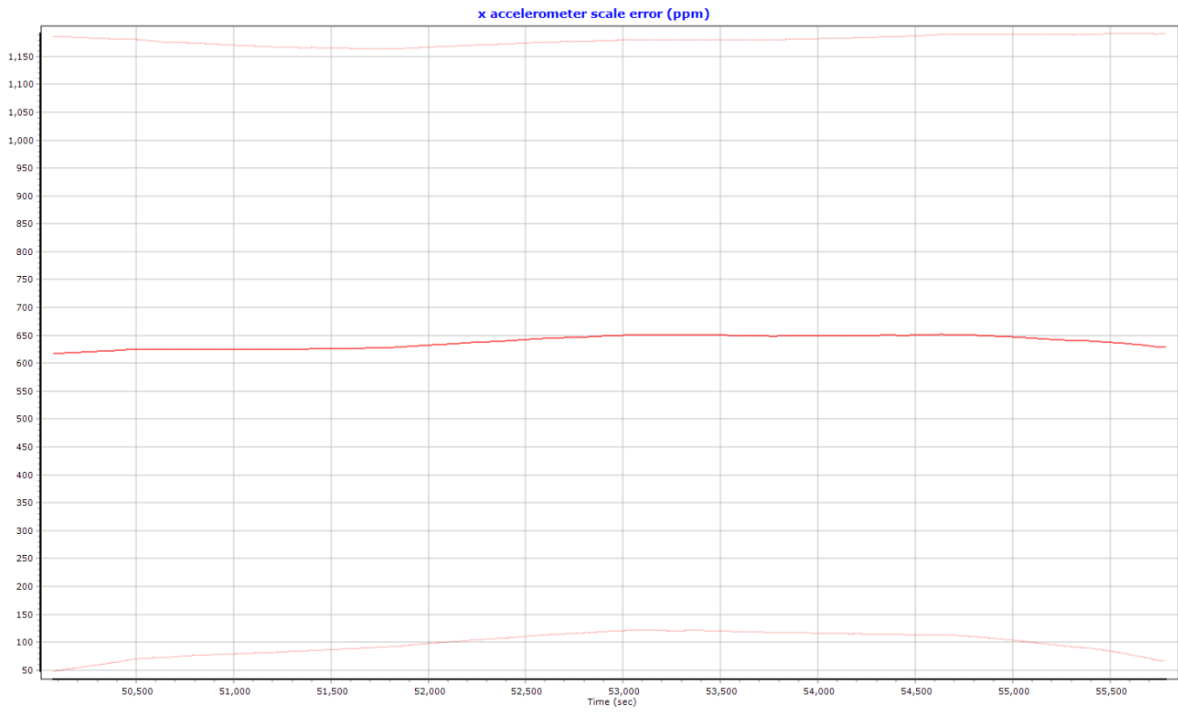
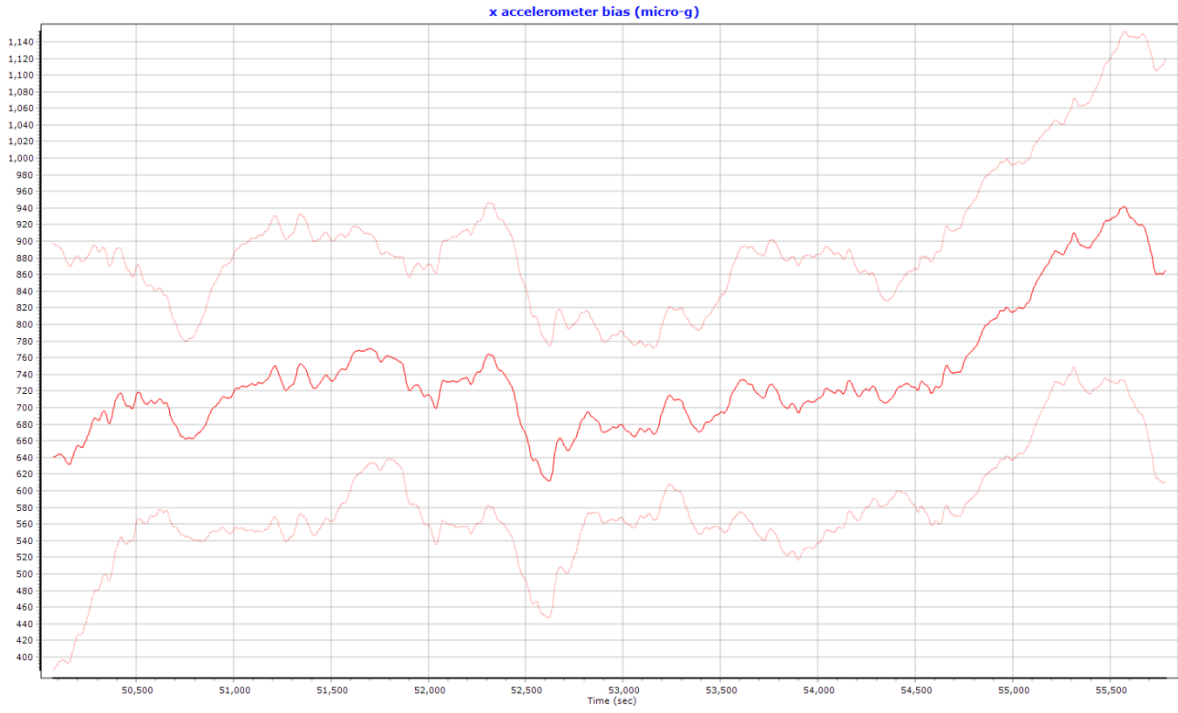
Entire time interval

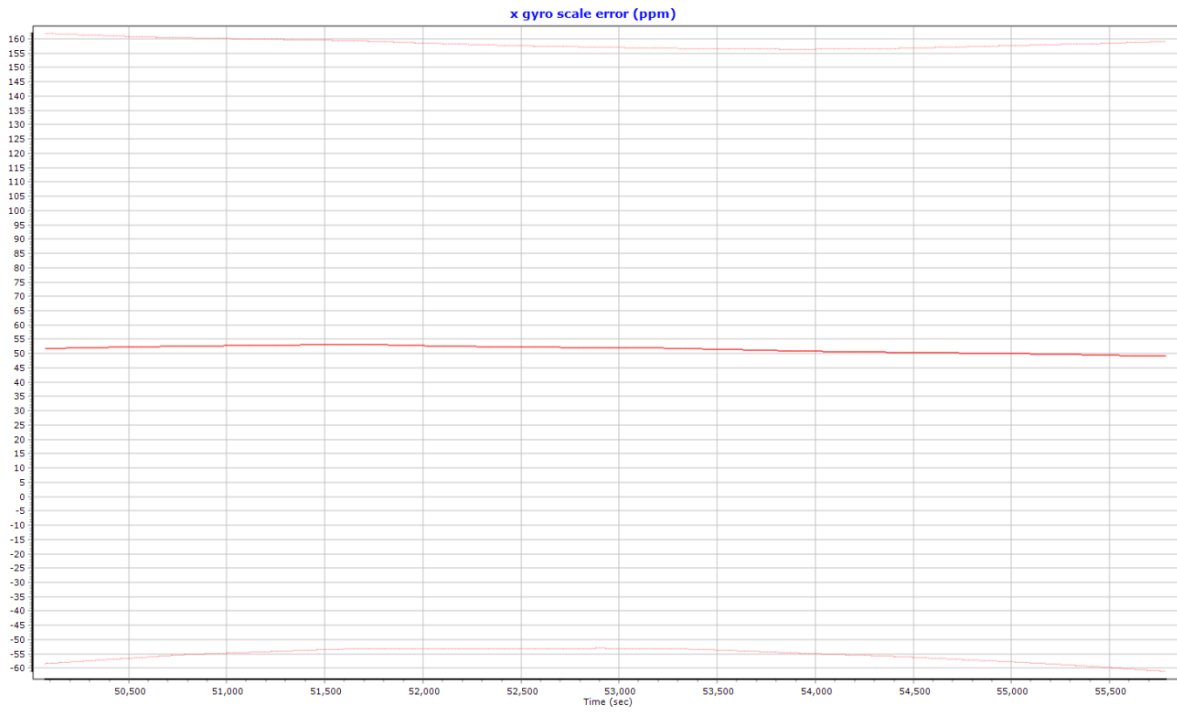
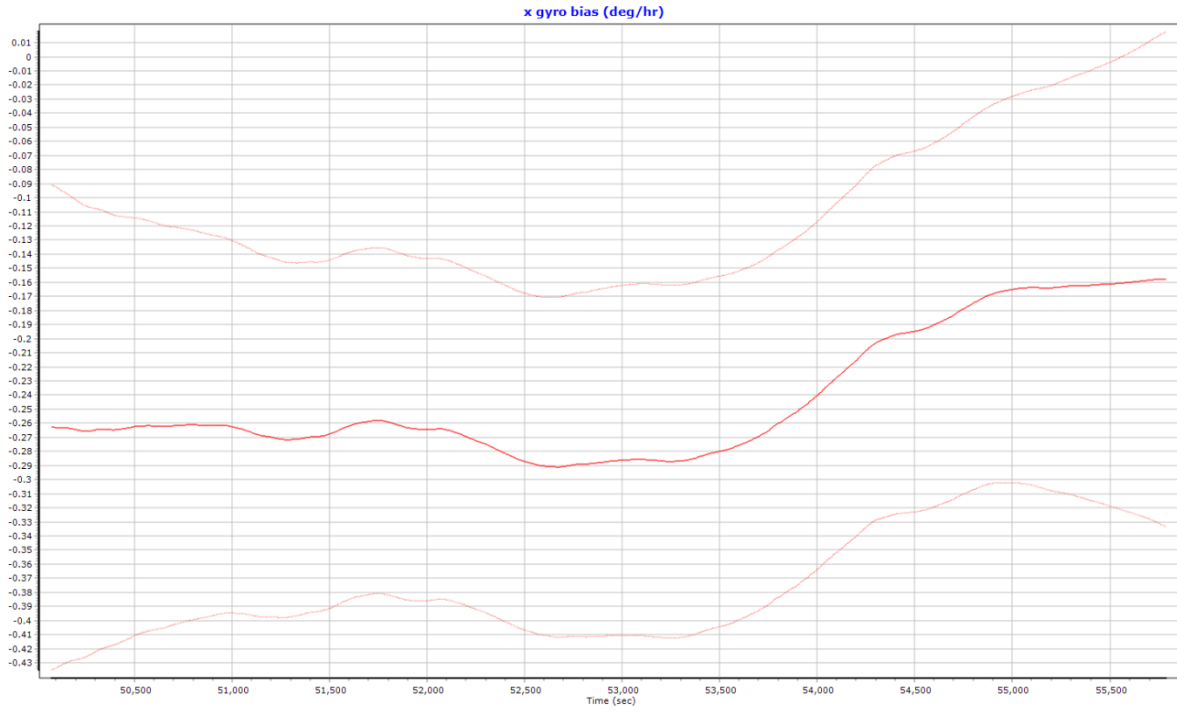
Seconds of start week

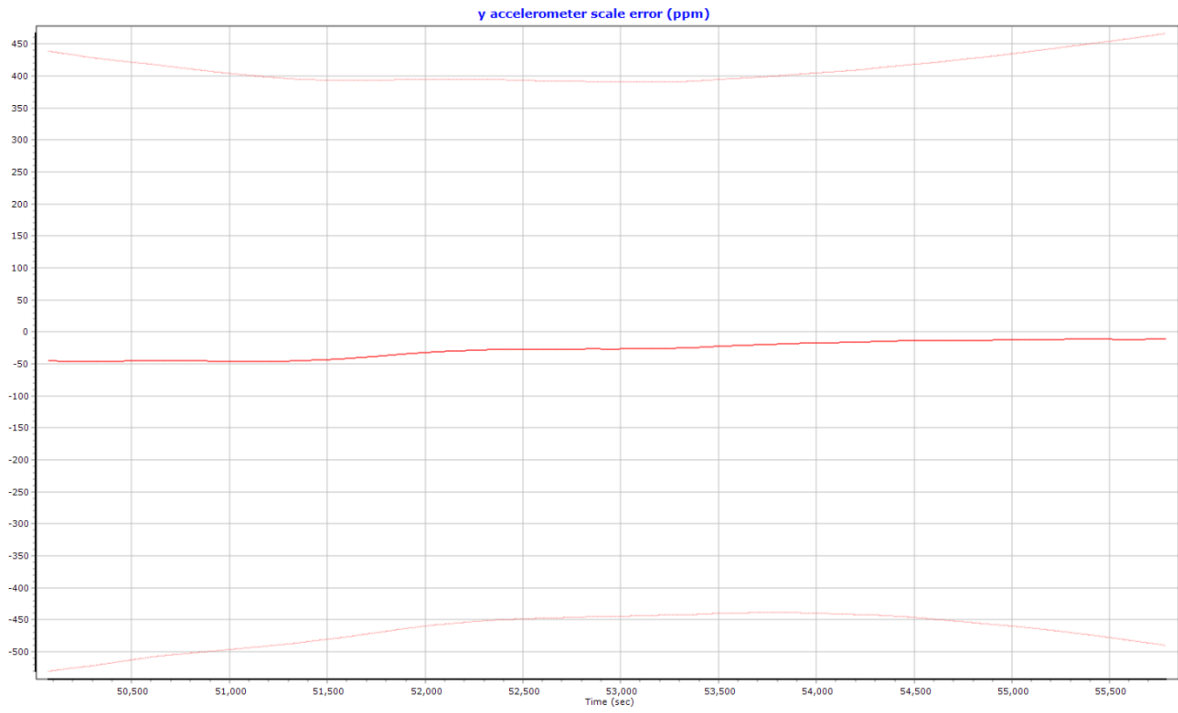
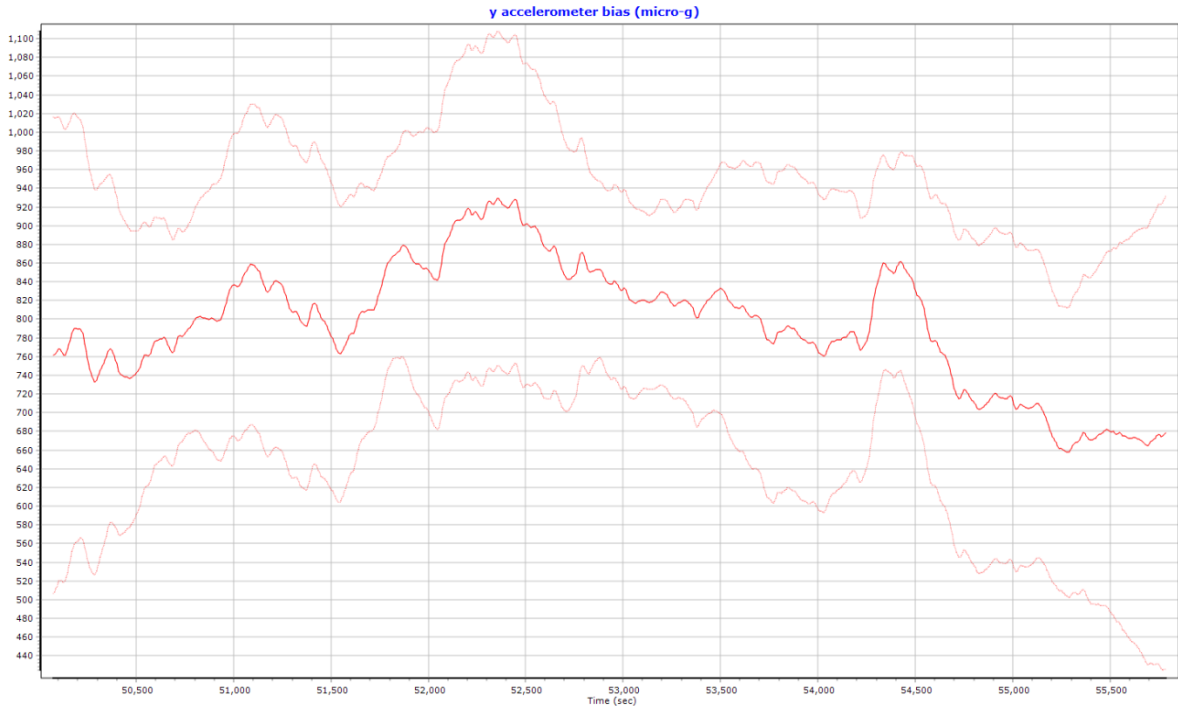
UTC Offset: 18.000

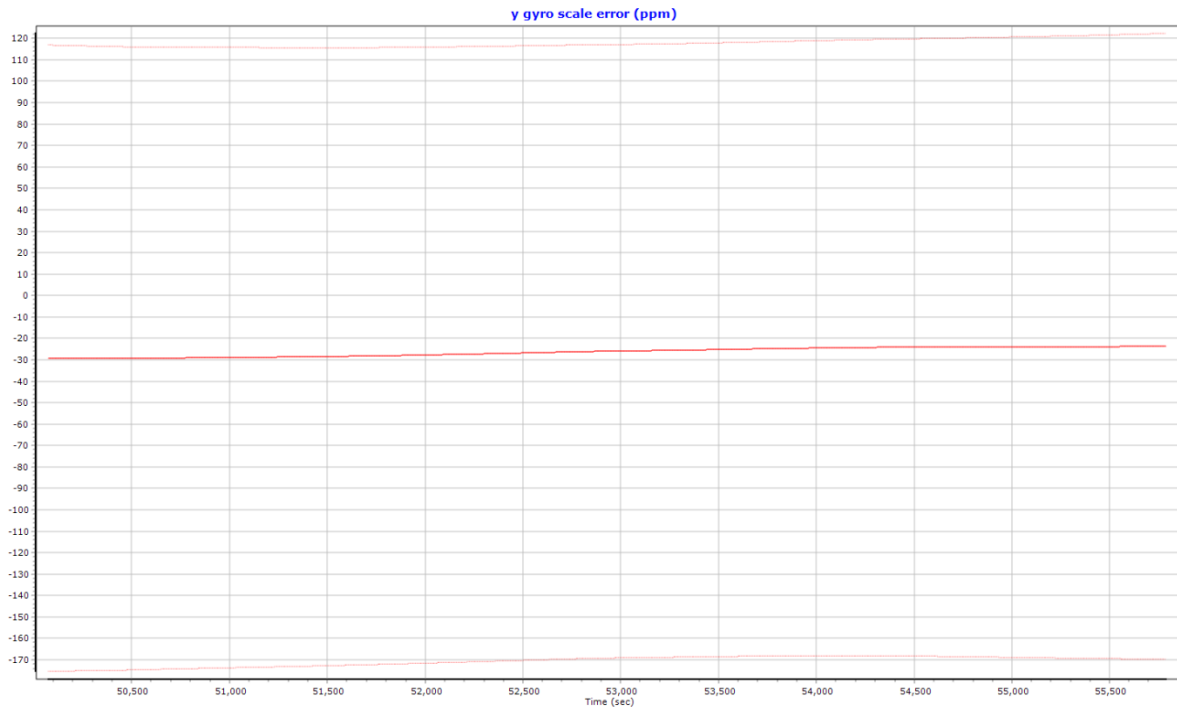
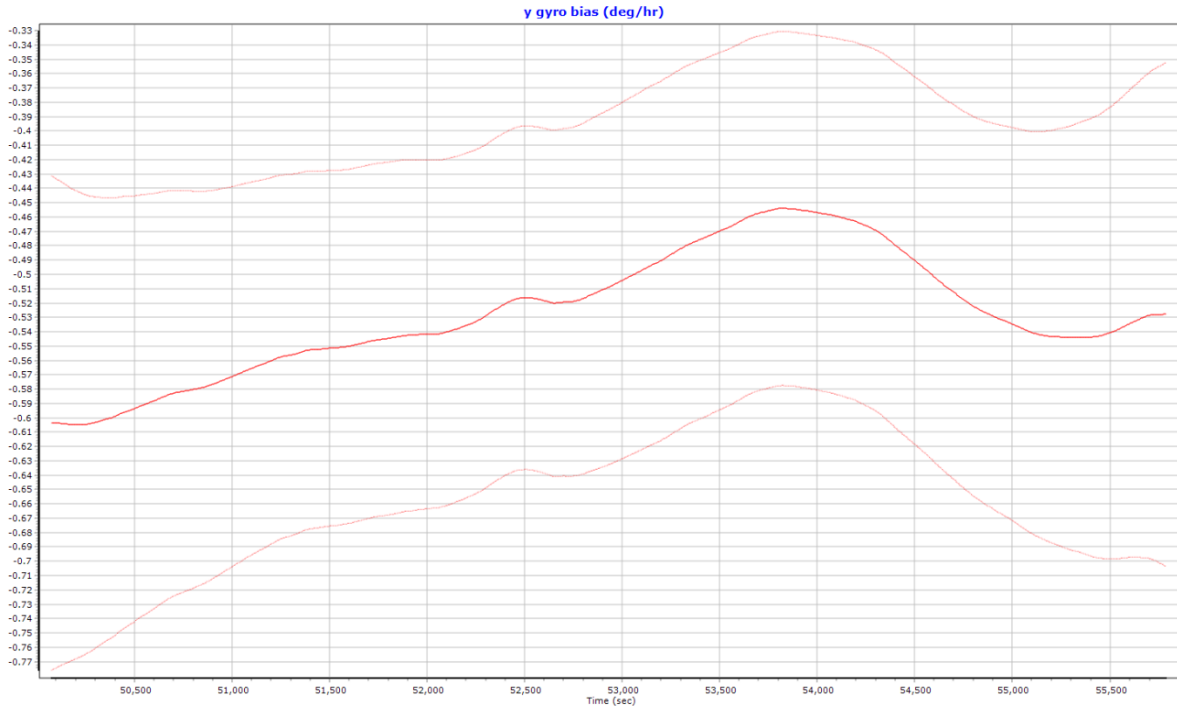
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

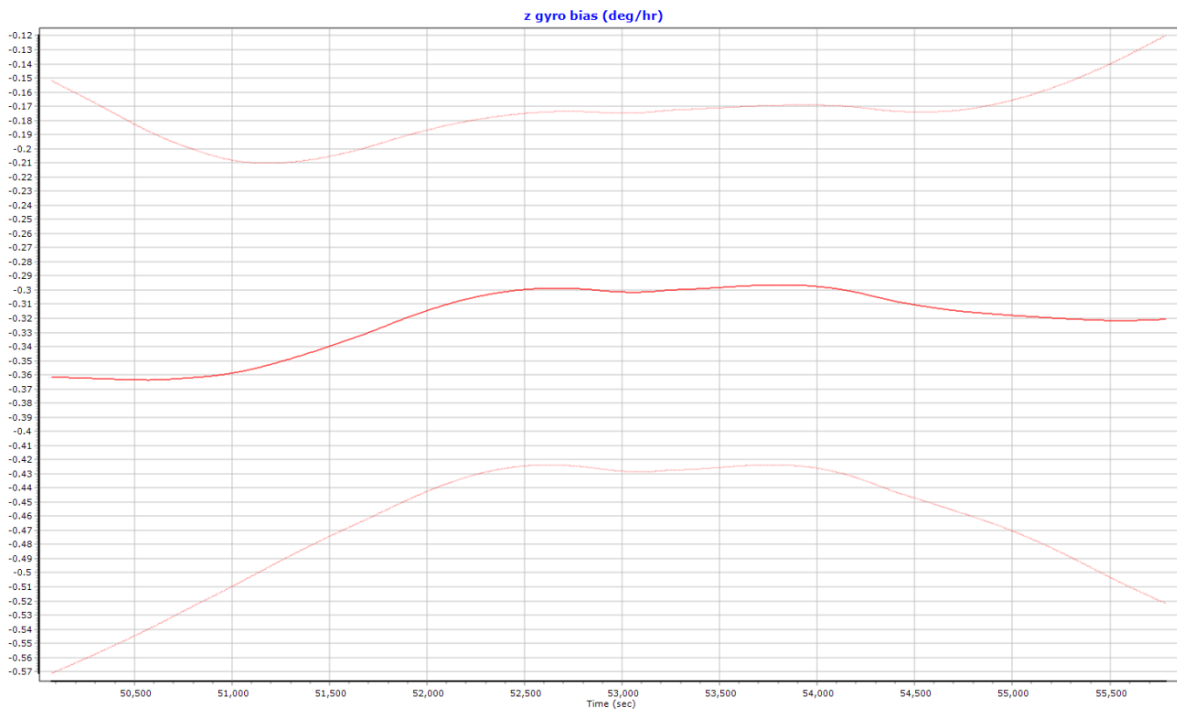
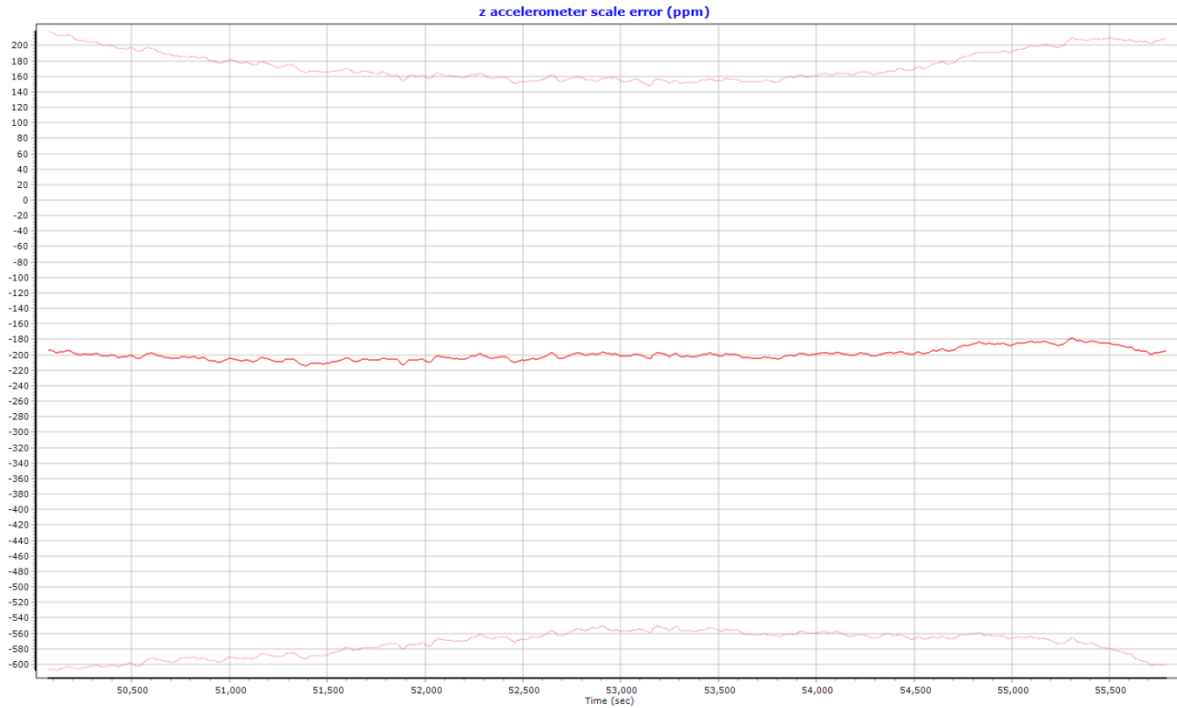
OK Cancel

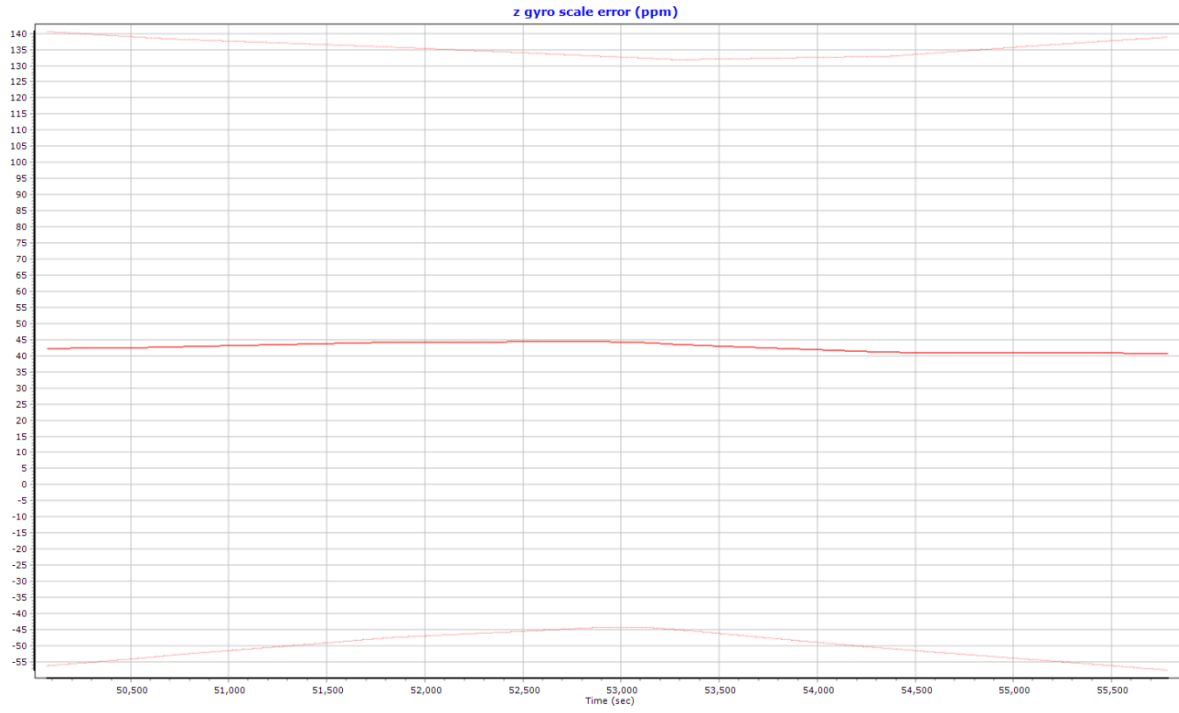




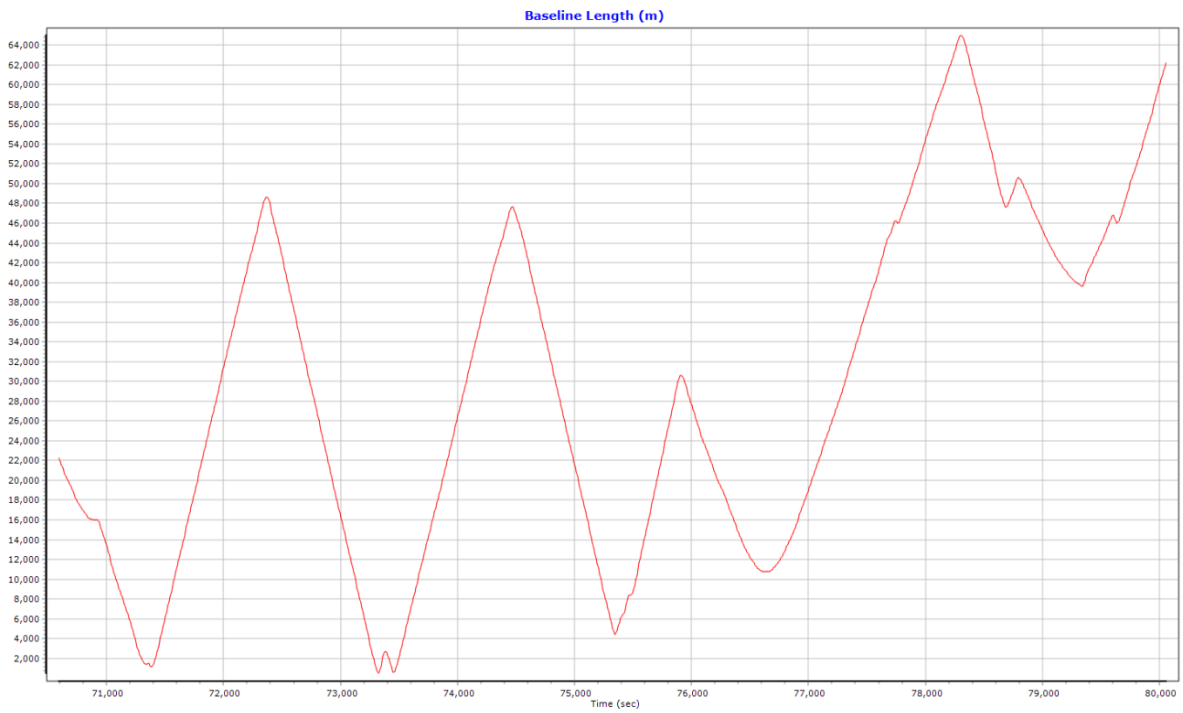
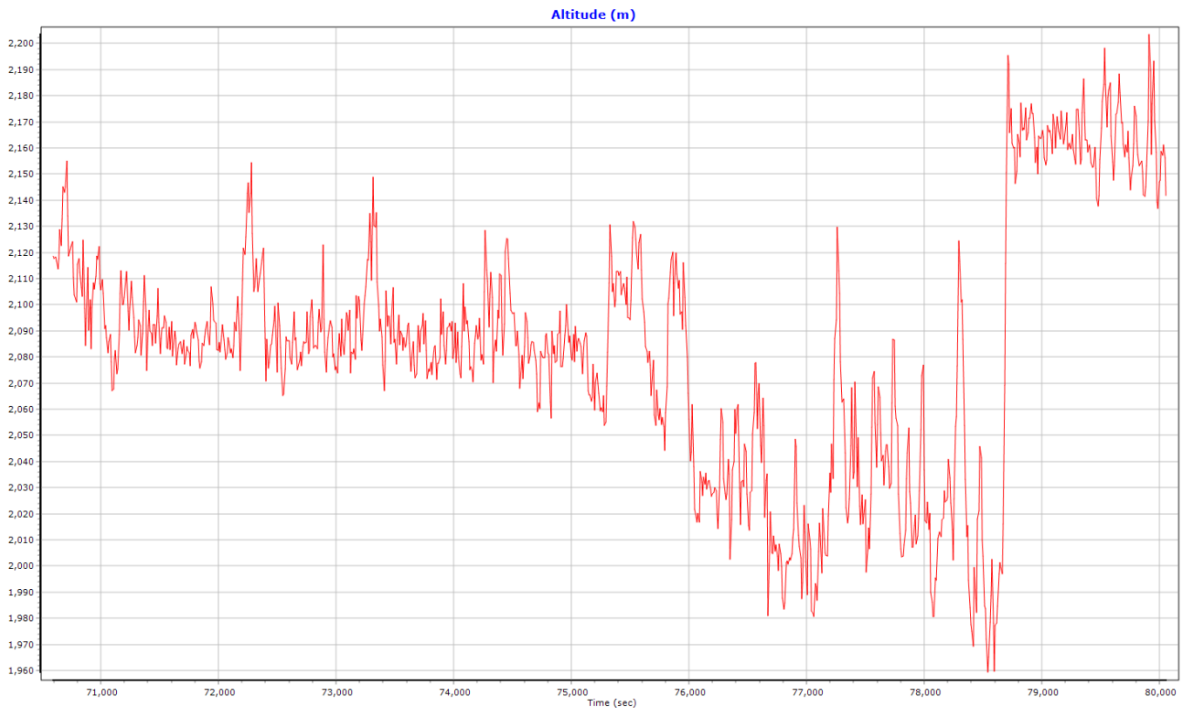


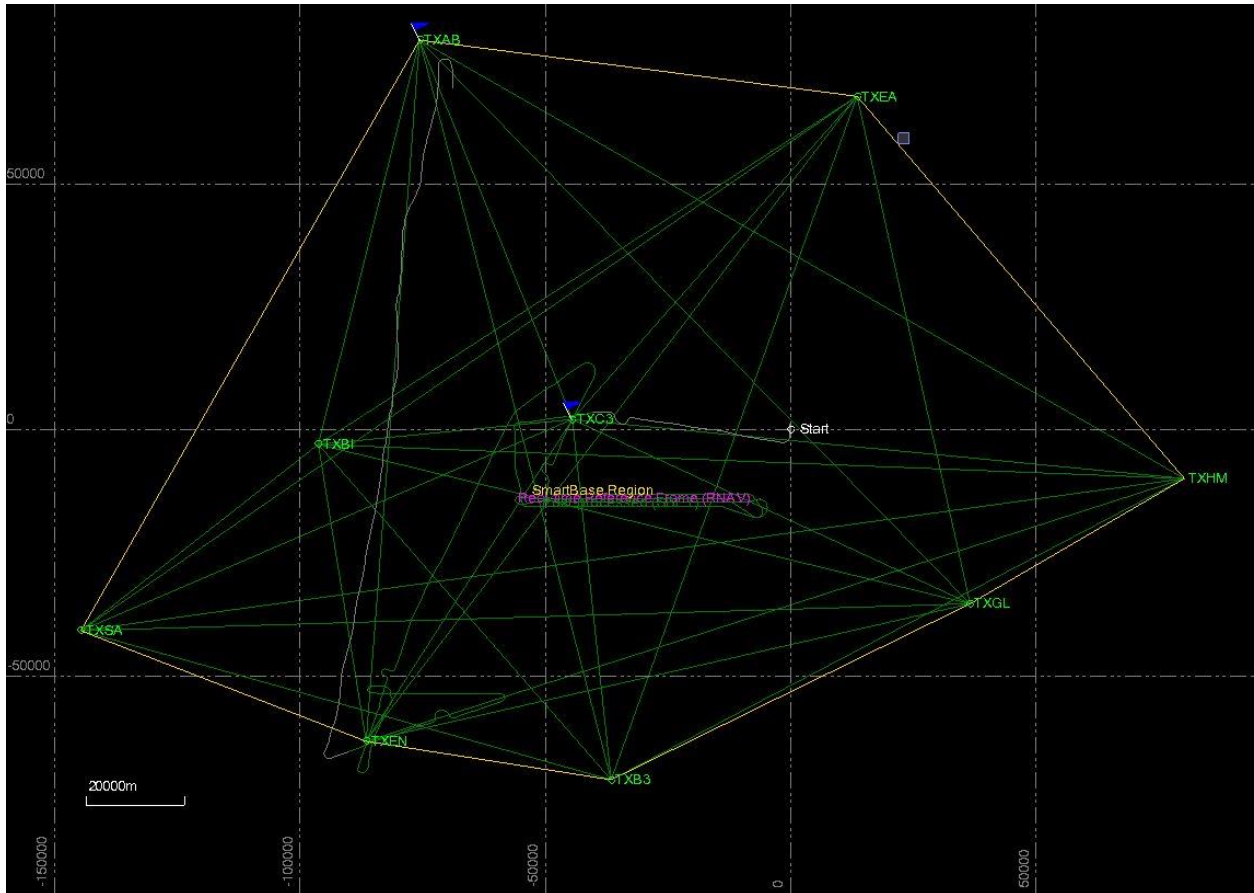


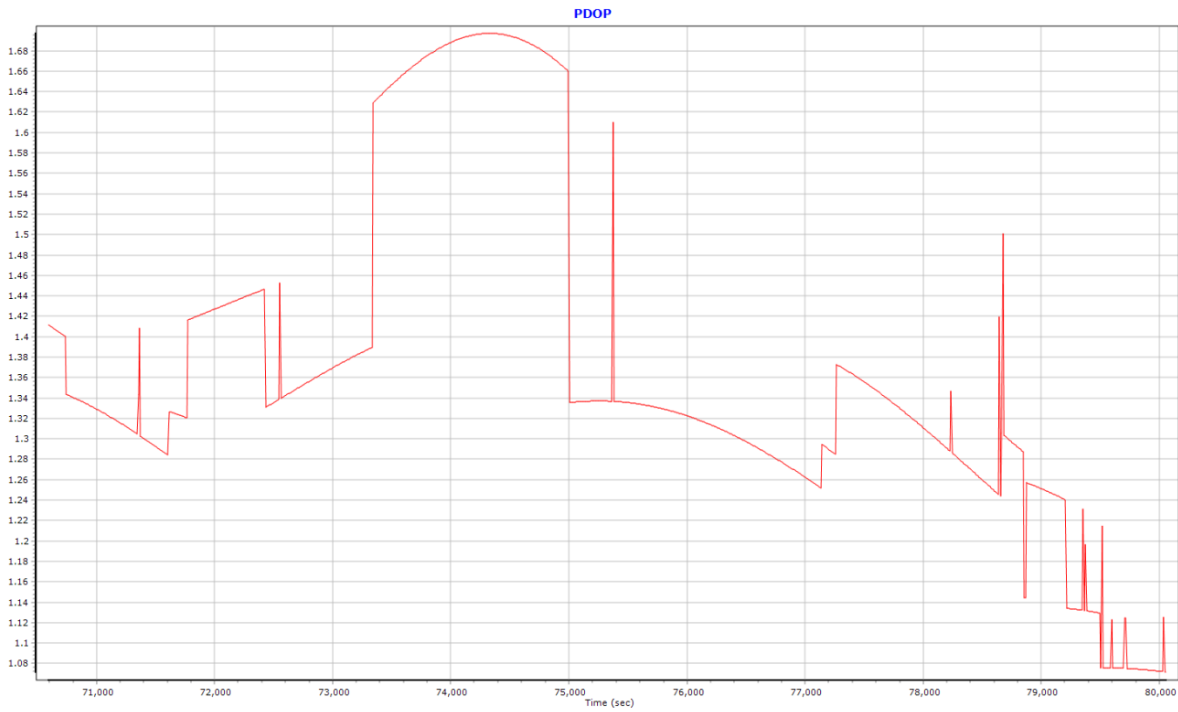
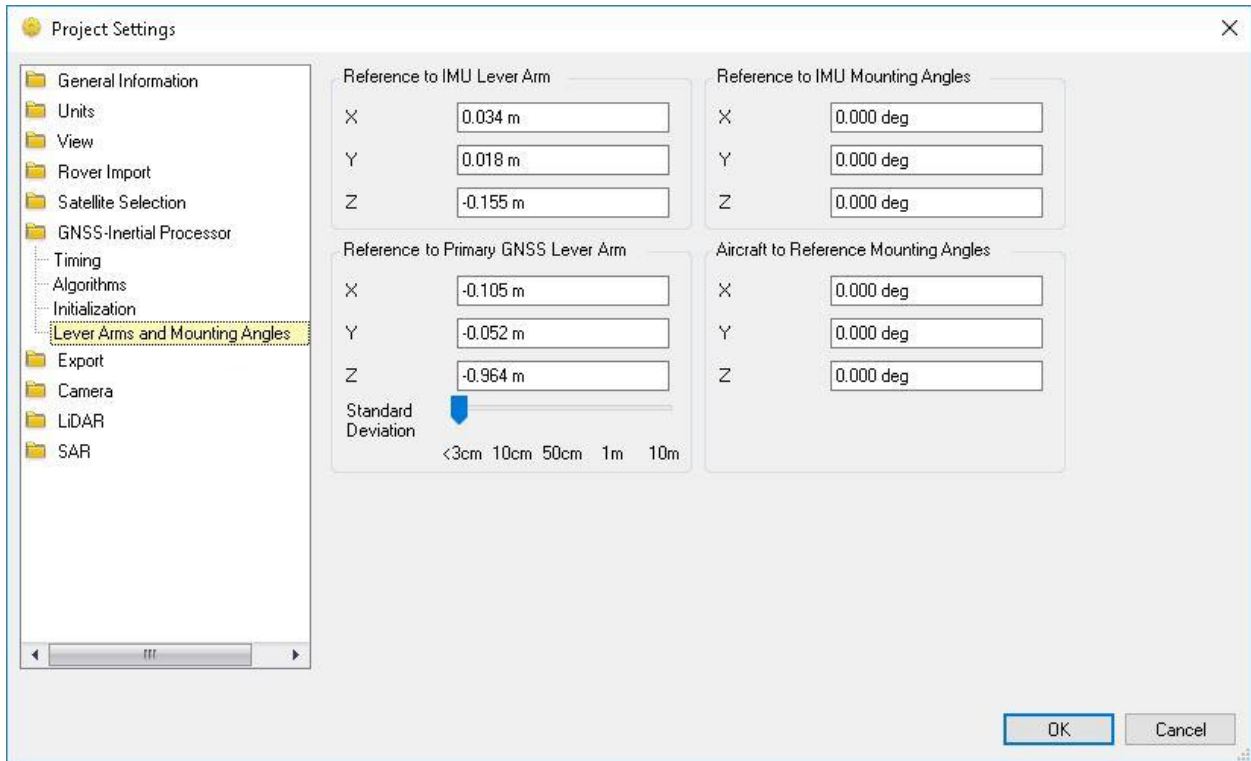


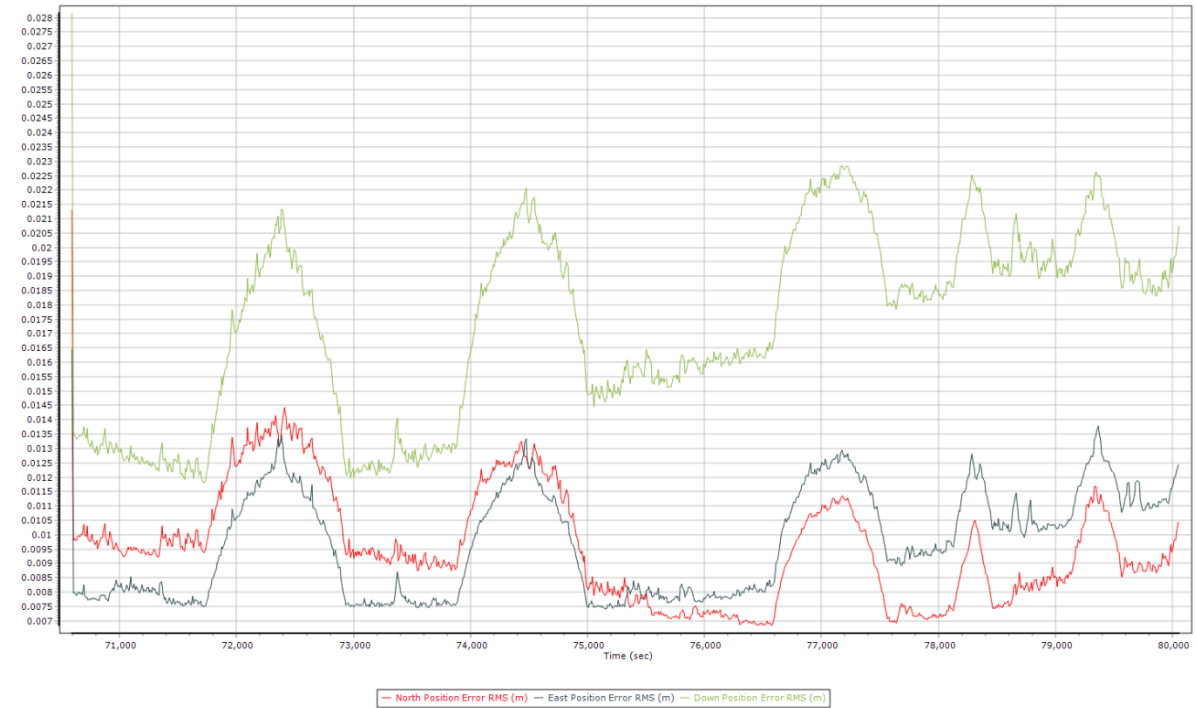
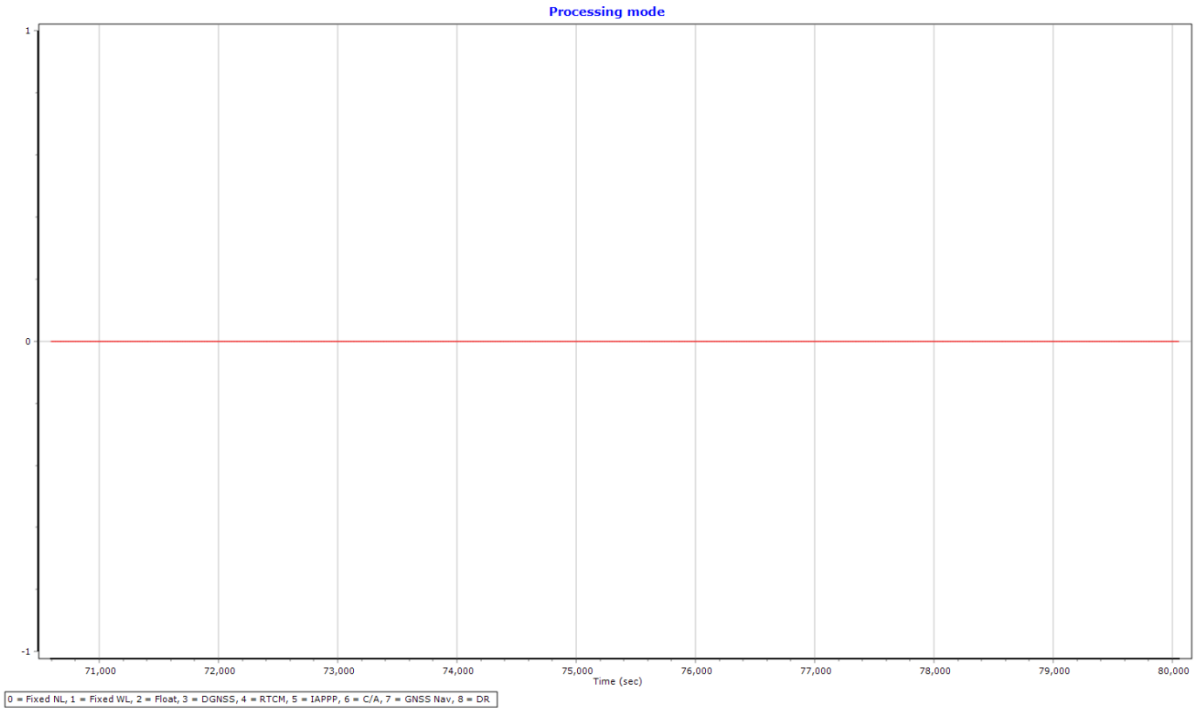


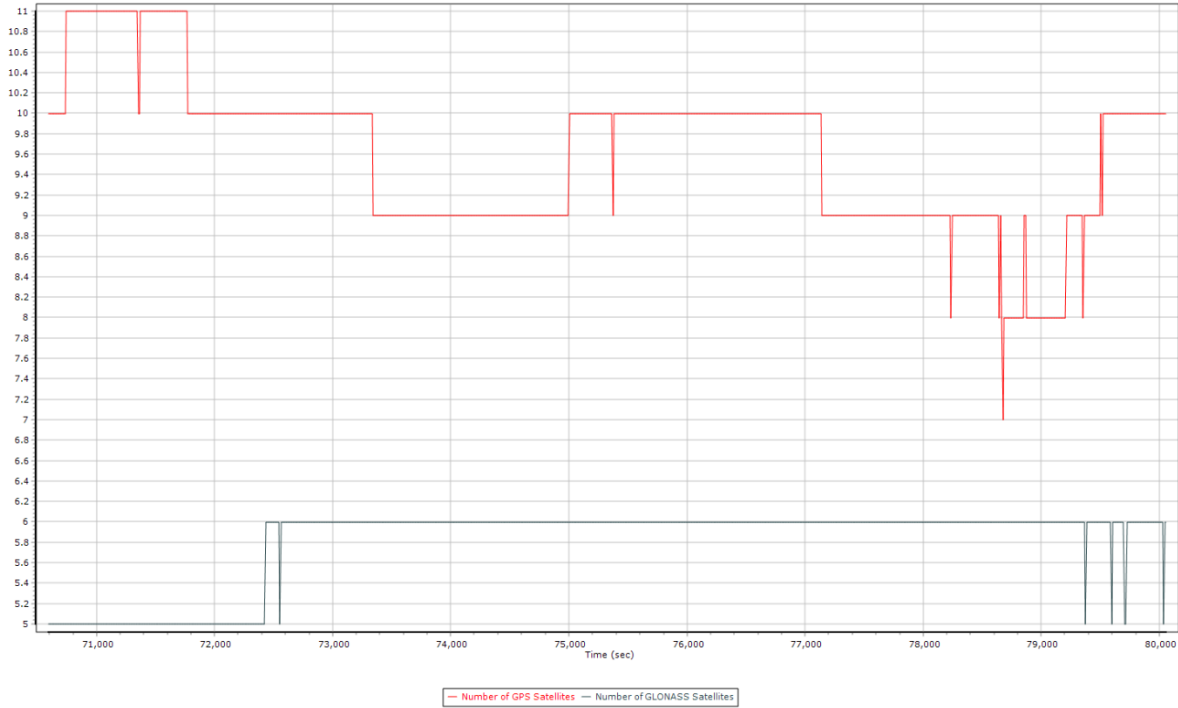
UNB18119B











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

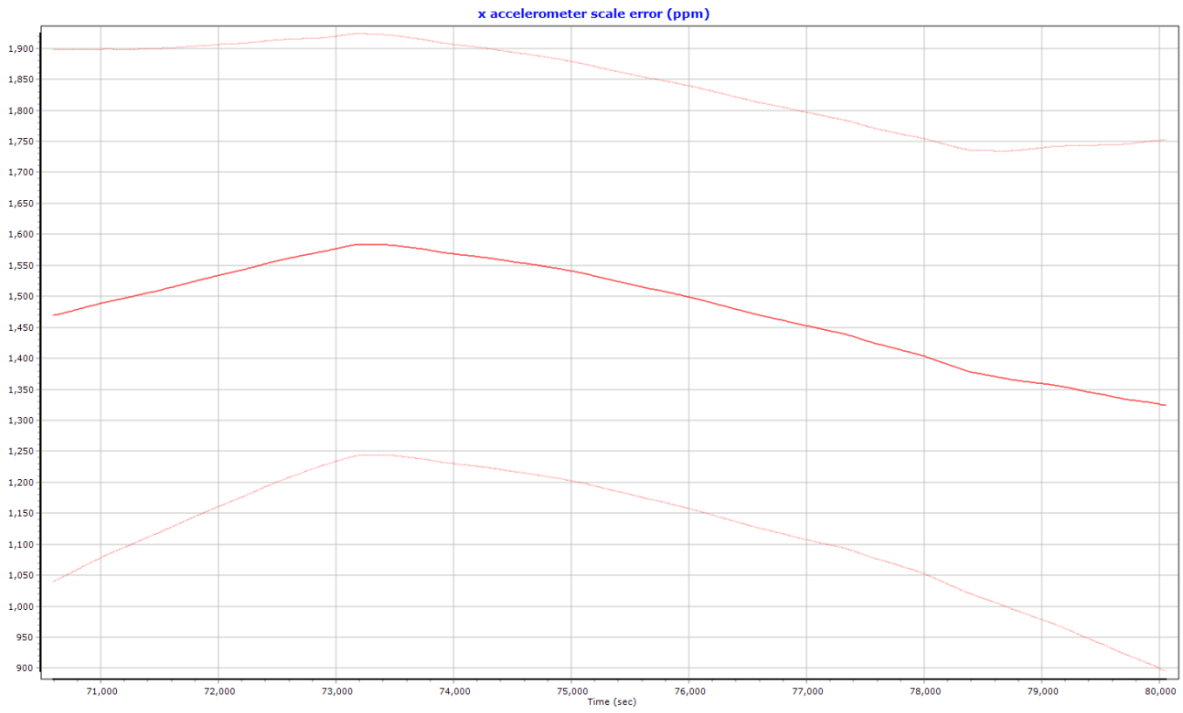
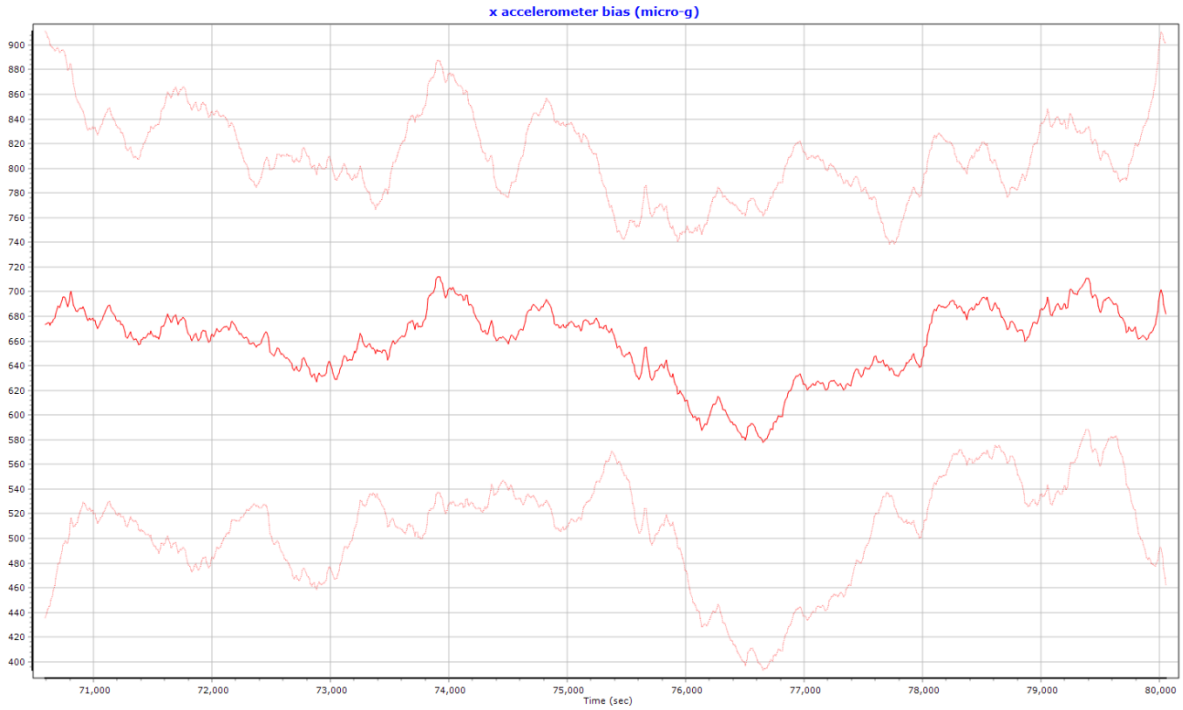
Start: 70590.969
End: 80071.328

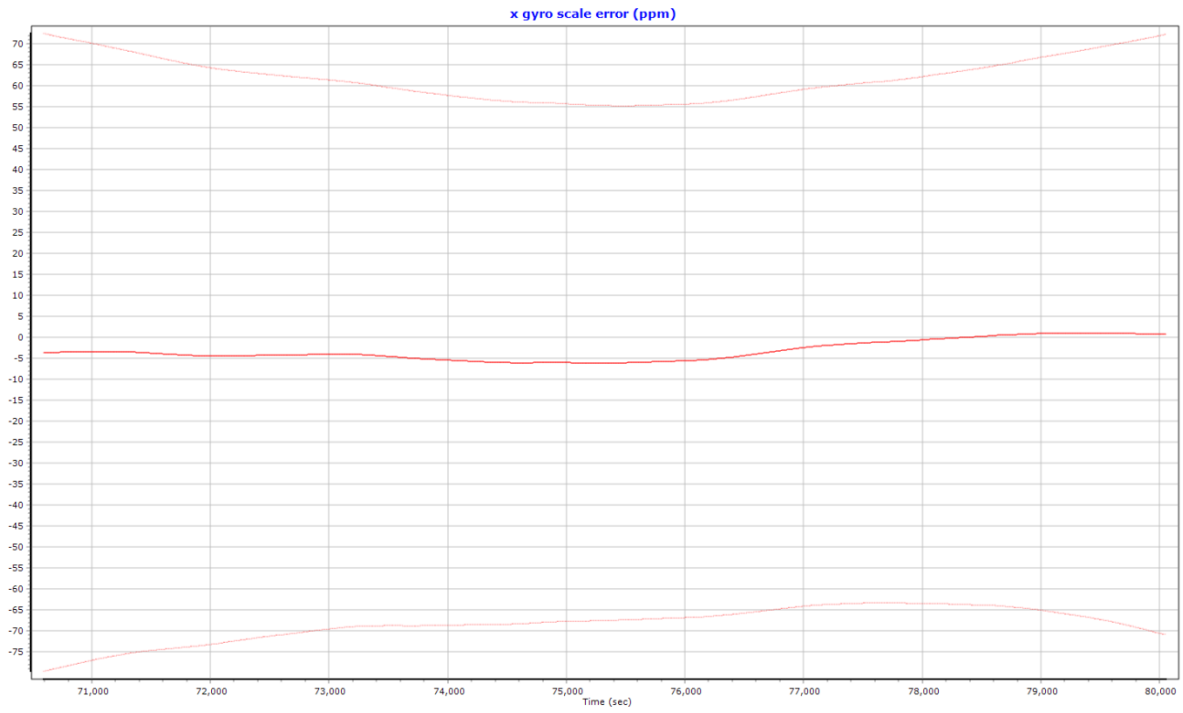
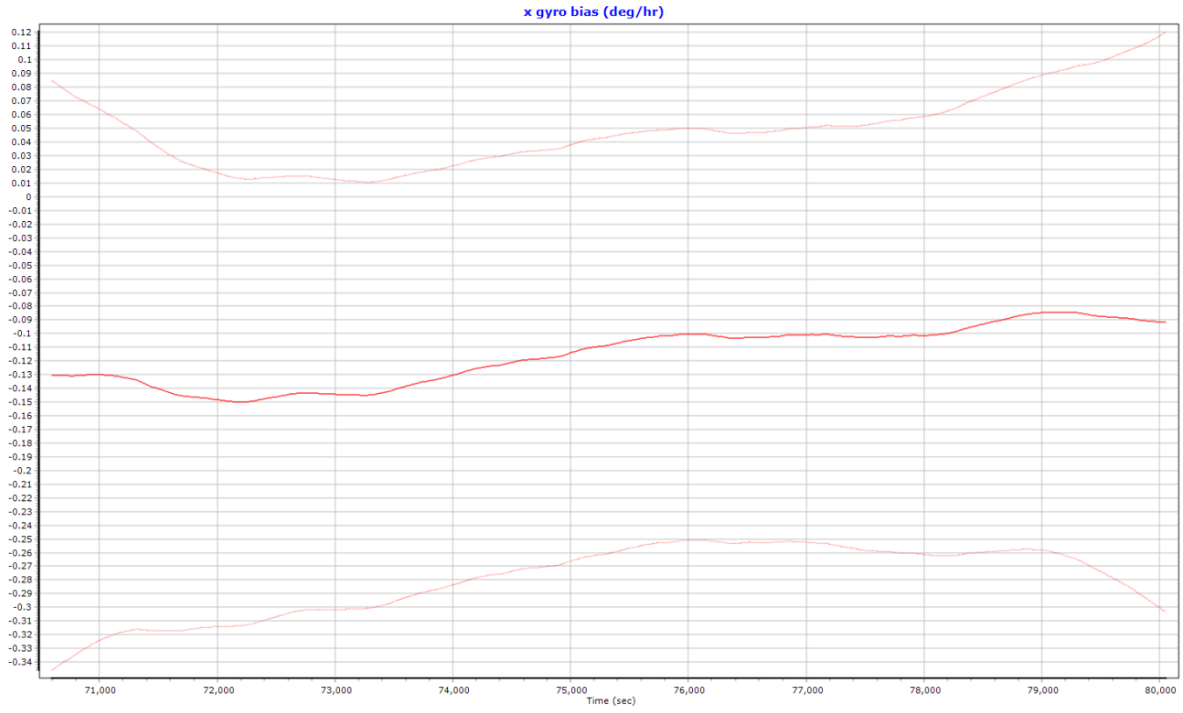
Entire time interval
 Seconds of start week

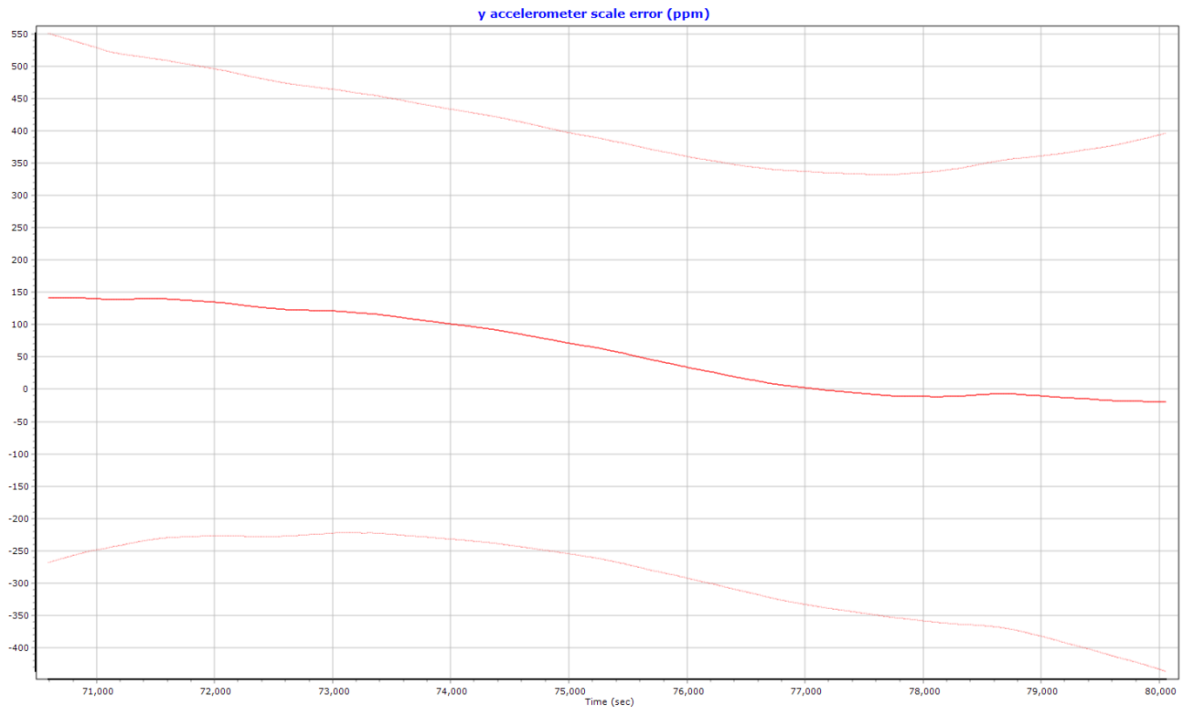
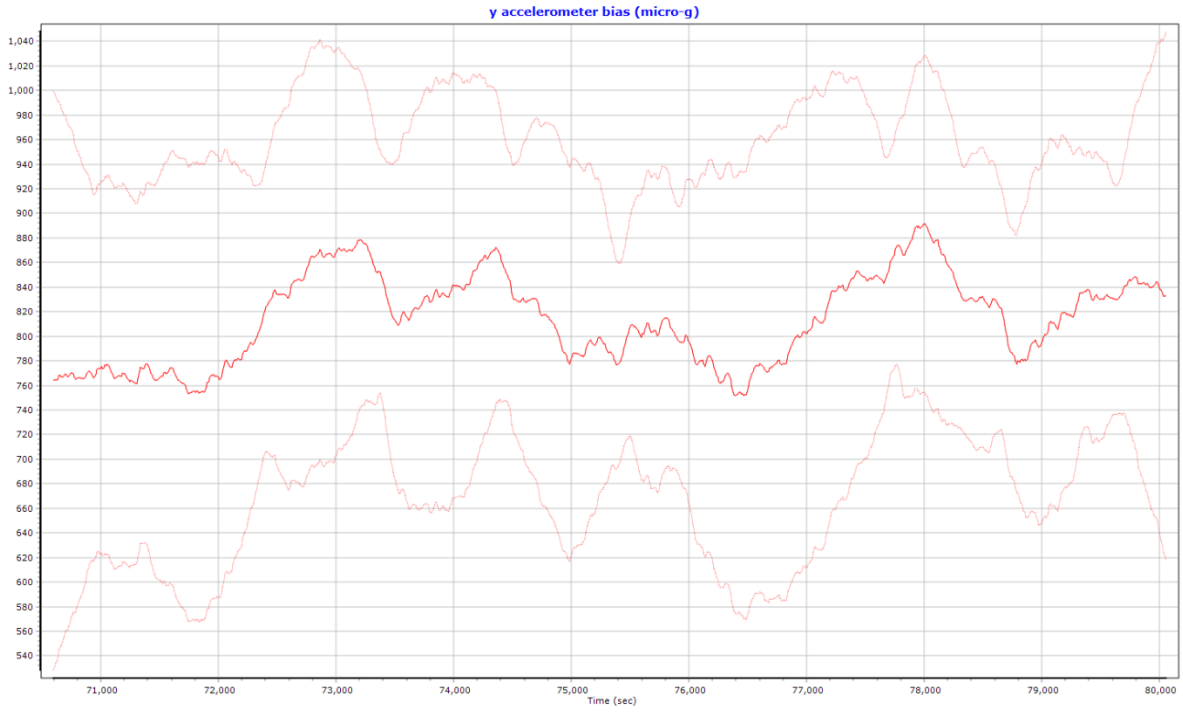
UTC Offset: 18.000

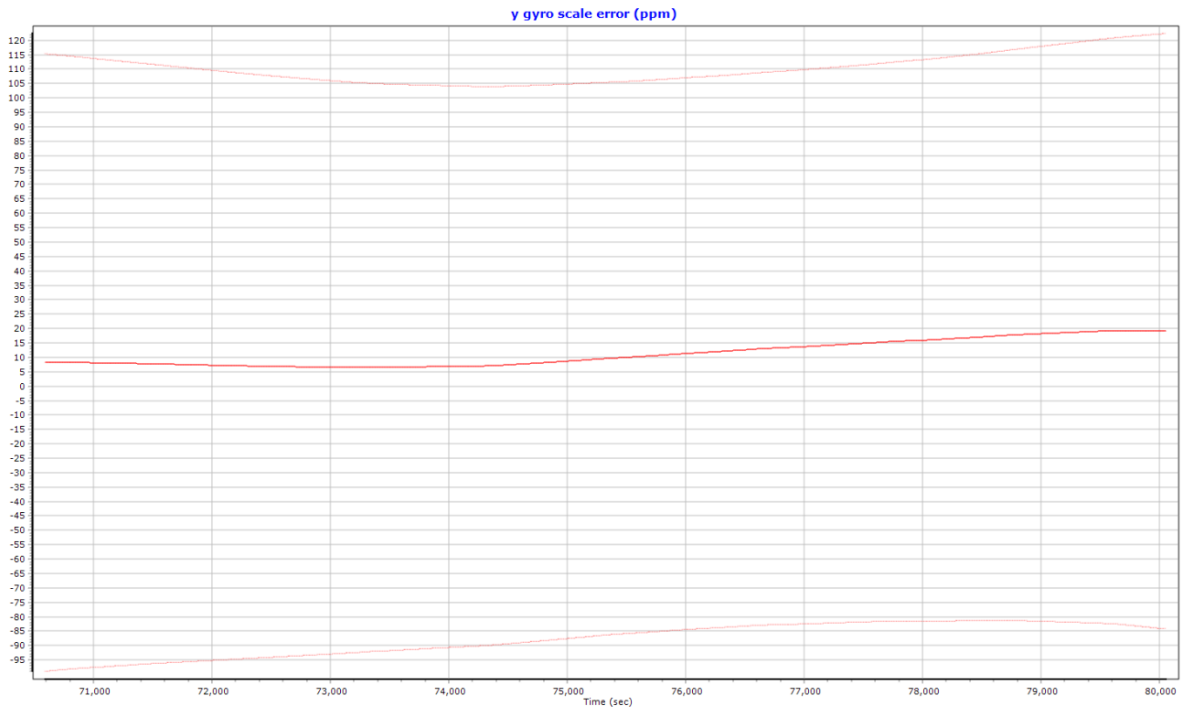
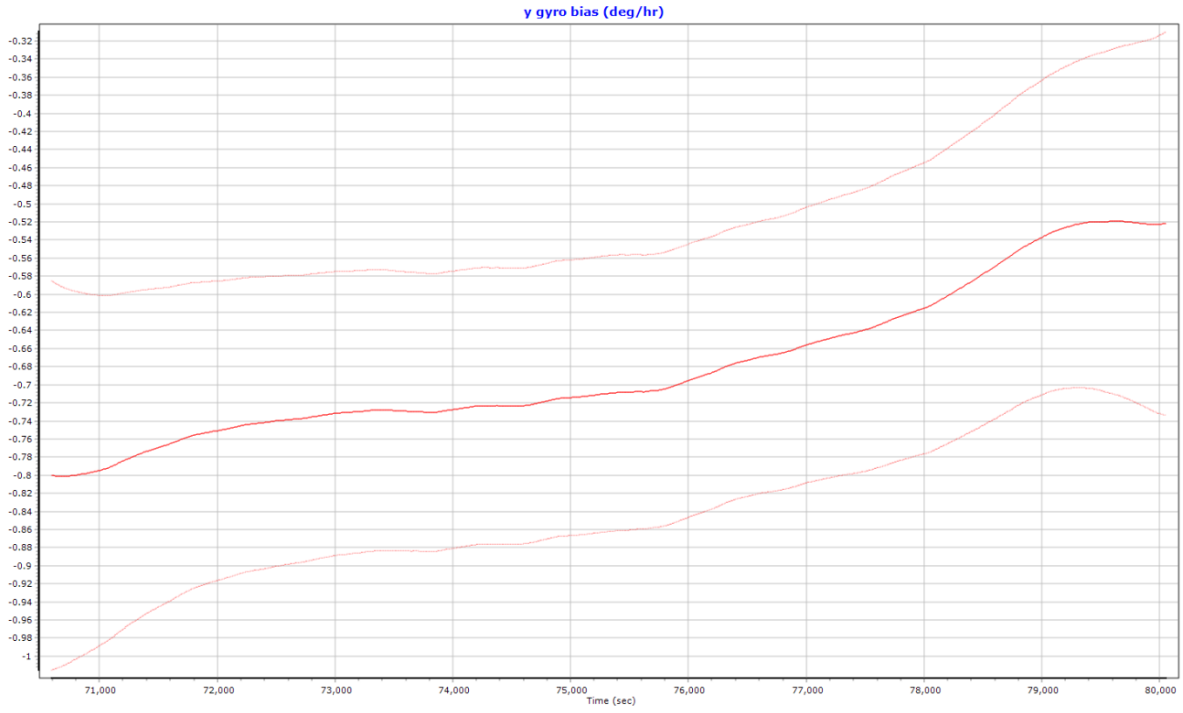
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

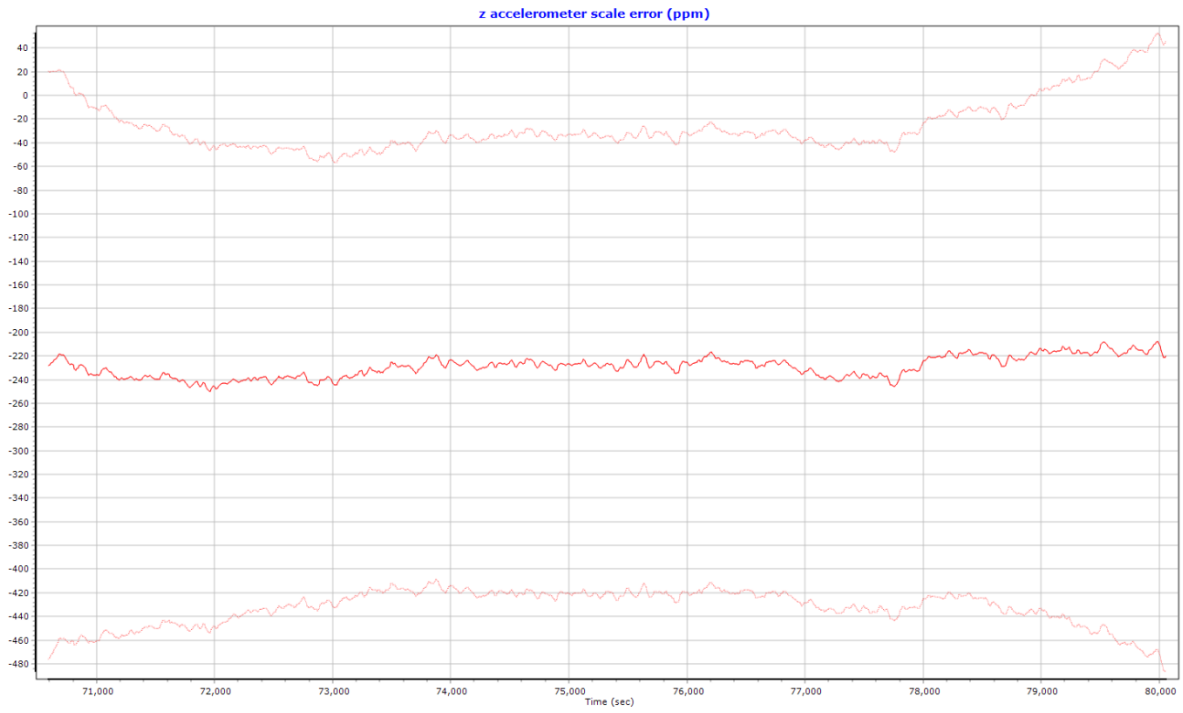
OK Cancel

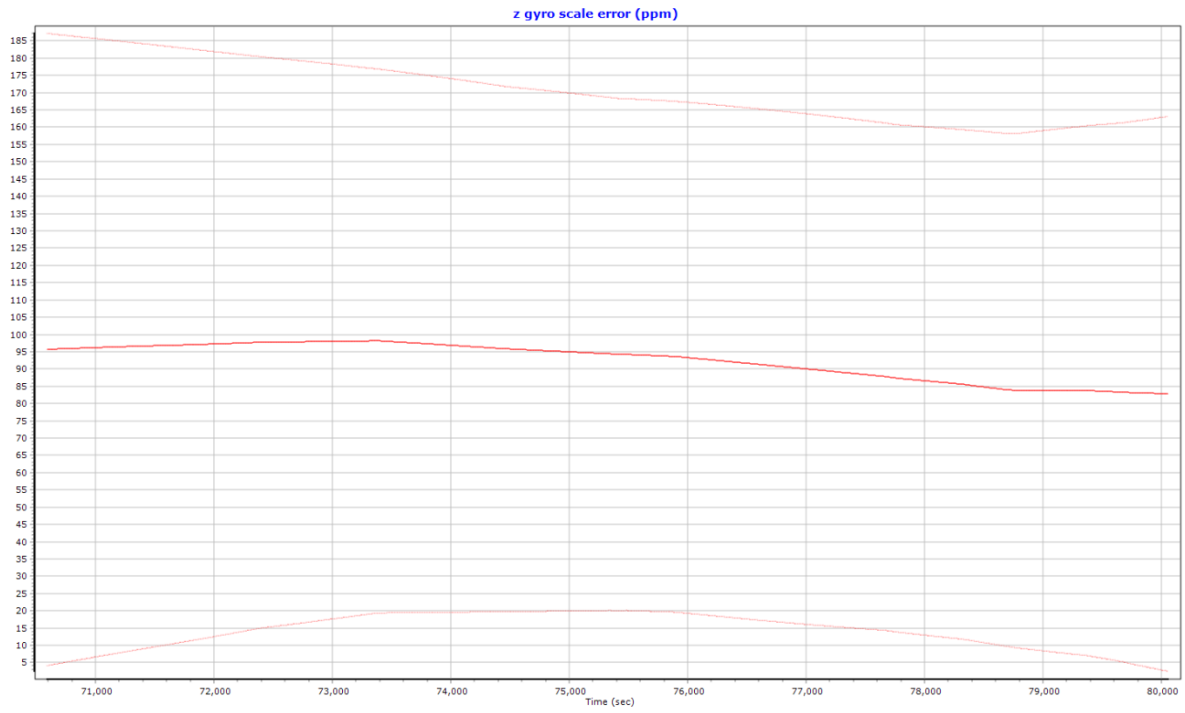
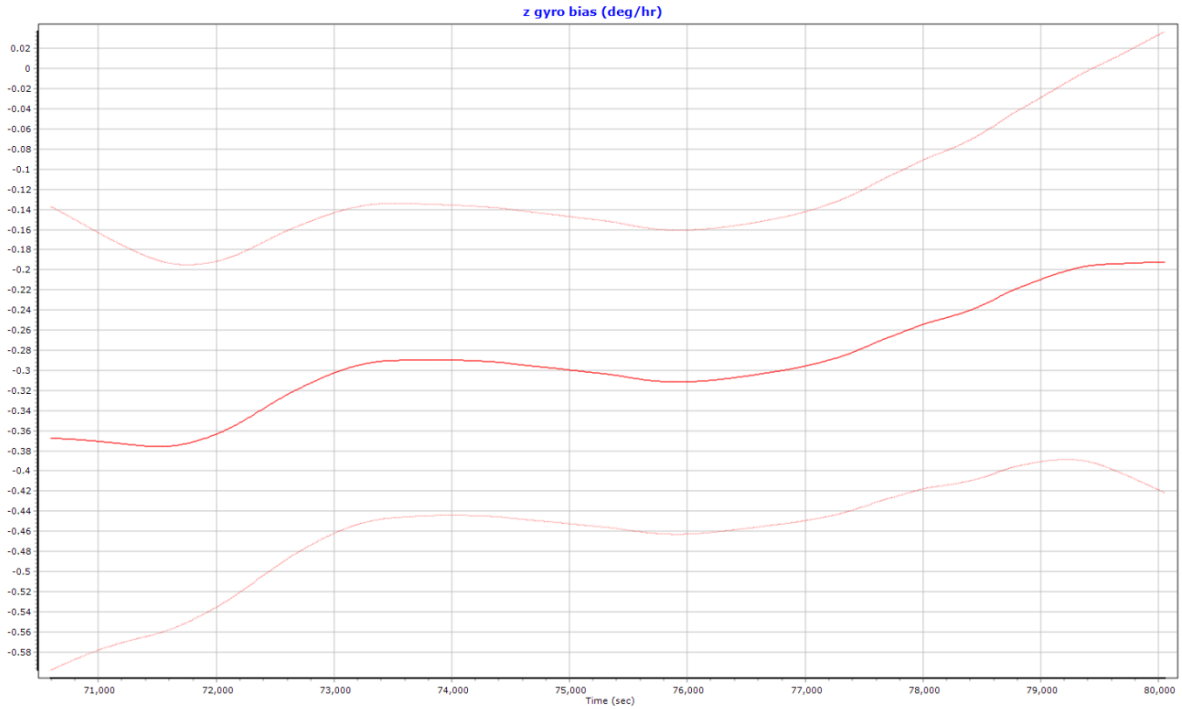




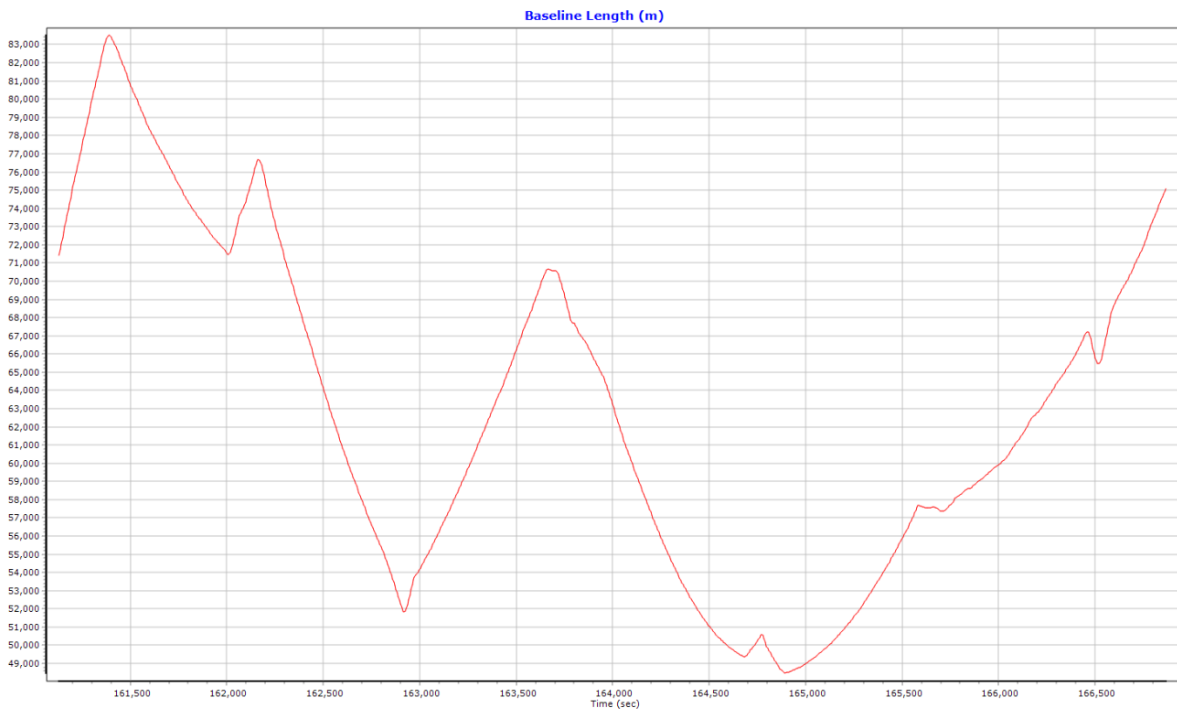
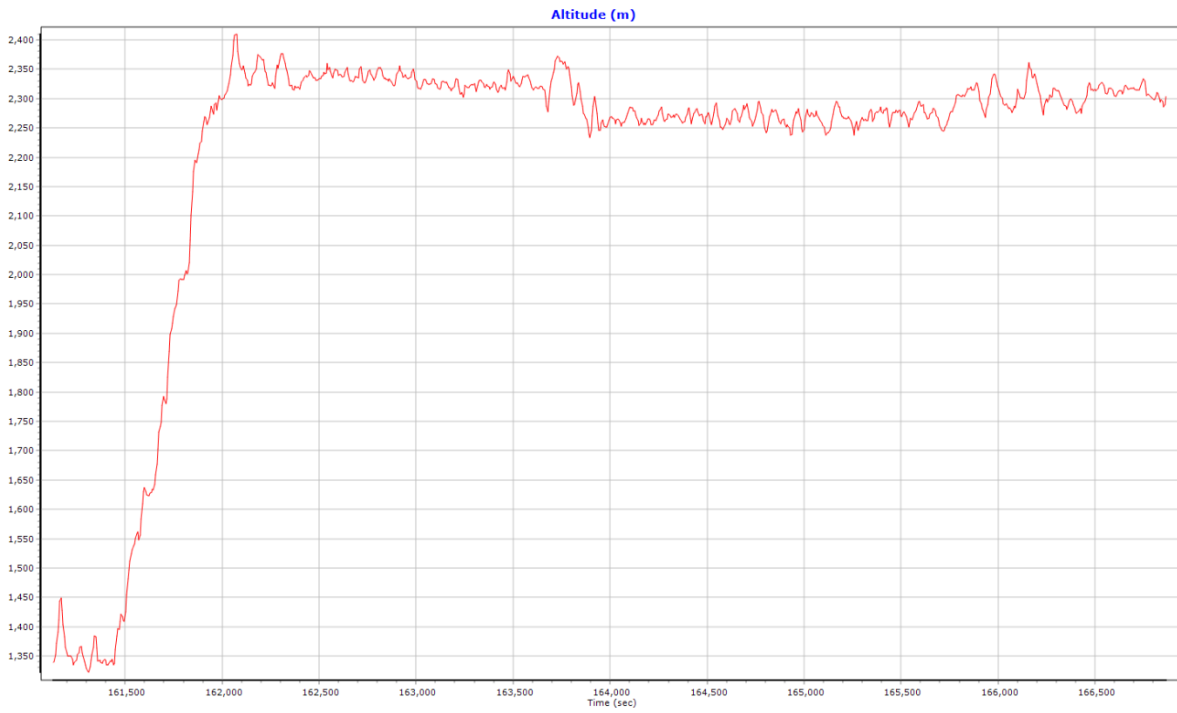


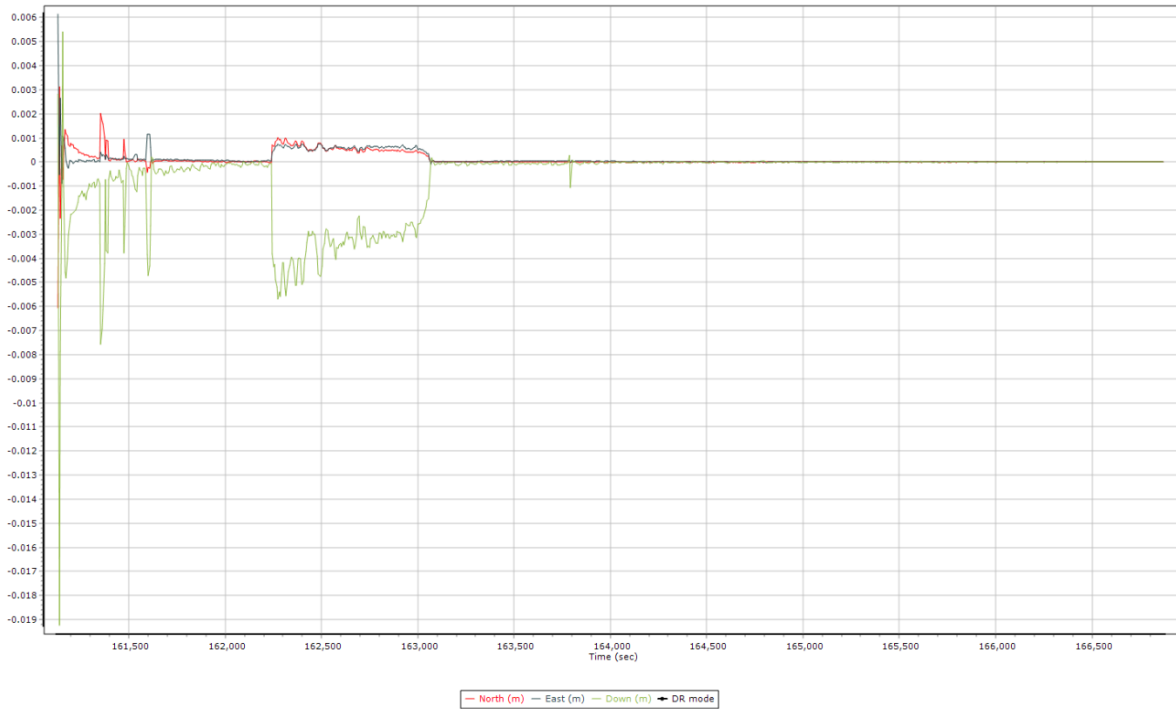
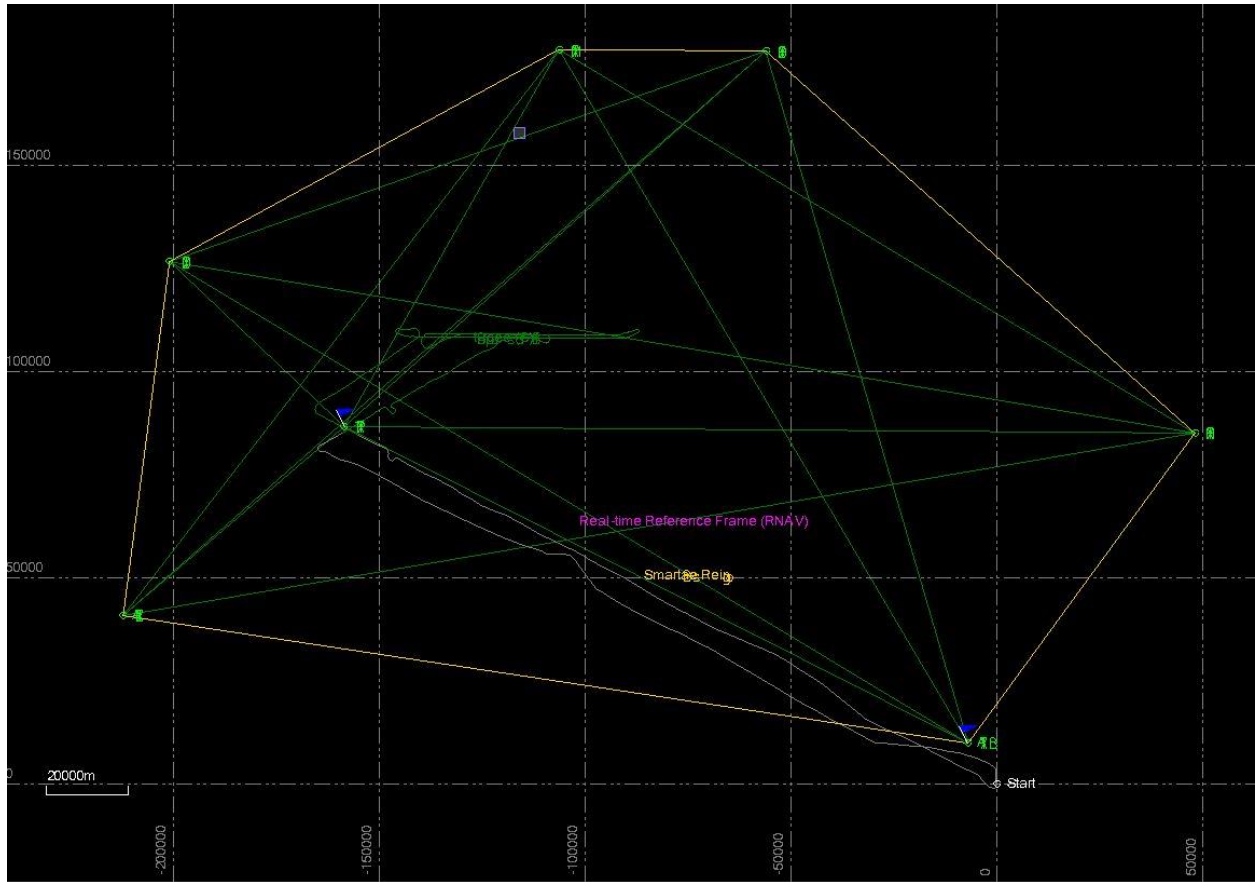






UNB18120A





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	0.034 m
Y	0.018 m
Z	-0.155 m

Reference to IMU Mounting Angles

X	0.000 deg
Y	0.000 deg
Z	0.000 deg

Reference to Primary GNSS Lever Arm

X	-0.105 m
Y	-0.052 m
Z	-0.964 m

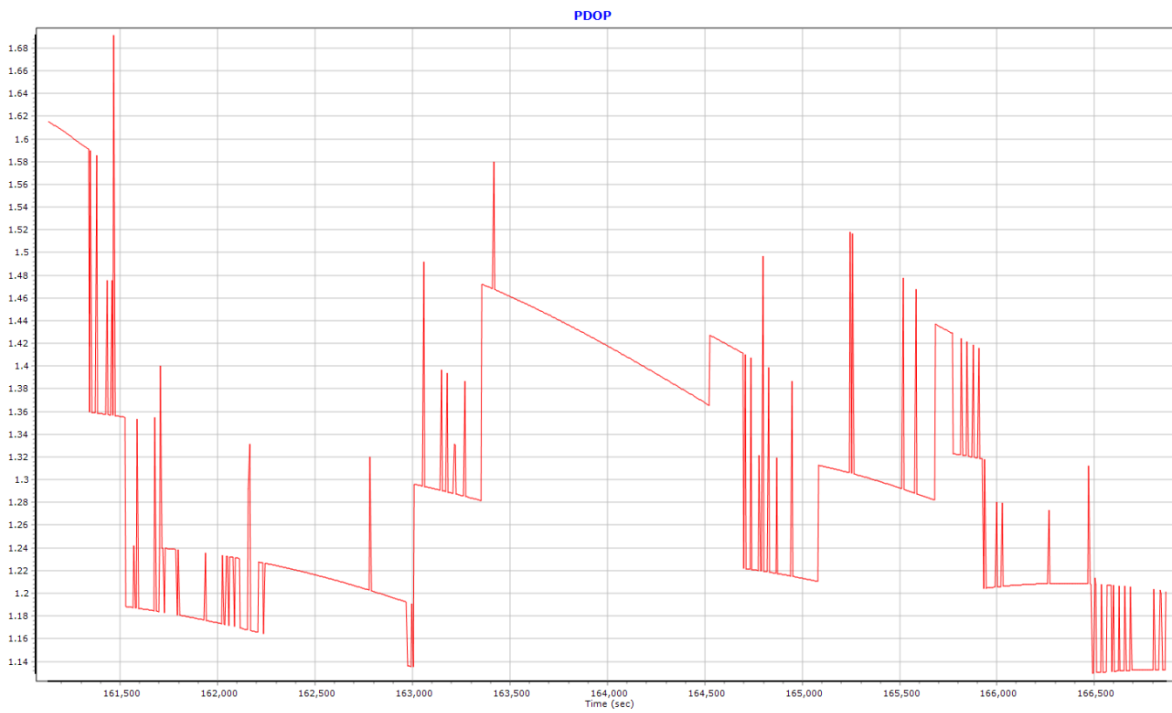
Aircraft to Reference Mounting Angles

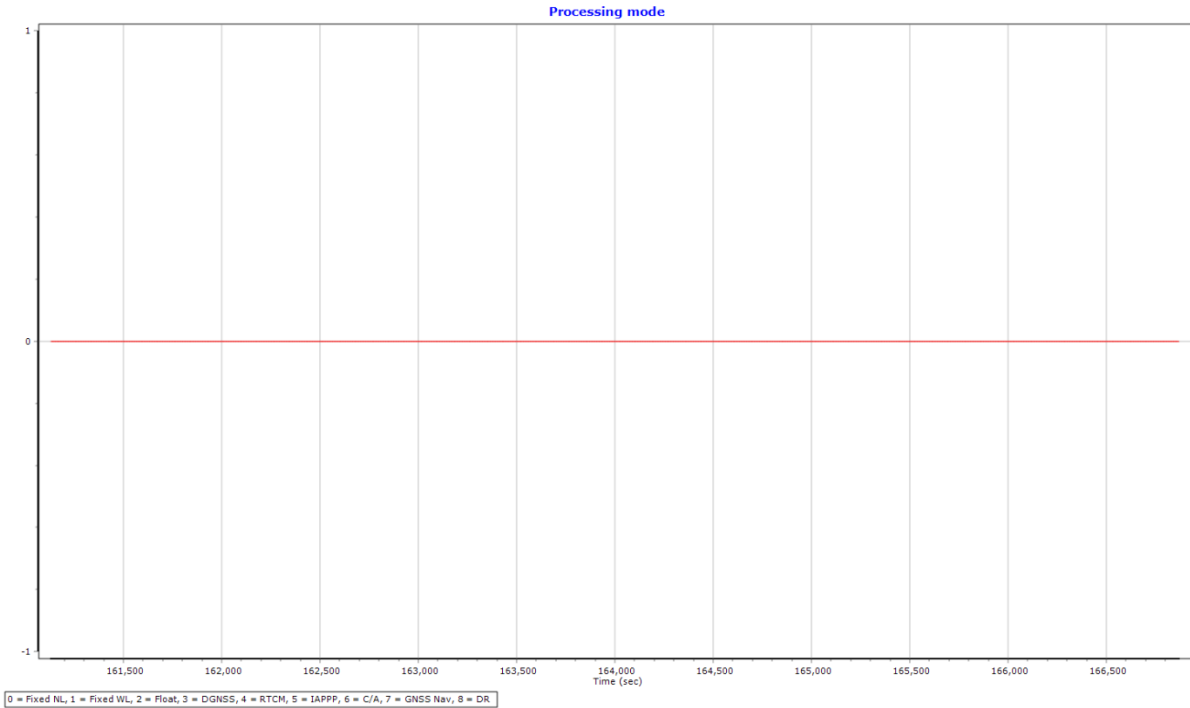
X	0.000 deg
Y	0.000 deg
Z	0.000 deg

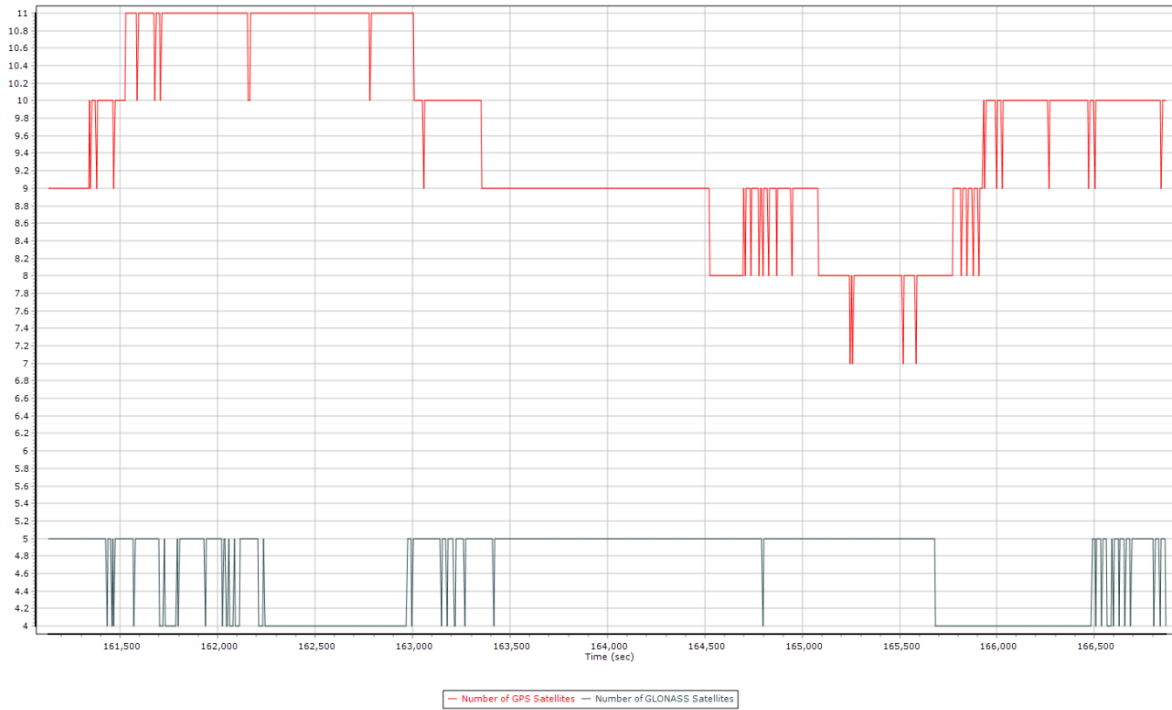
Standard Deviation

<3cm 10cm 50cm 1m 10m

OK Cancel







Project Settings [Close]

- 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: 161128.901 Data Incr. (sec)

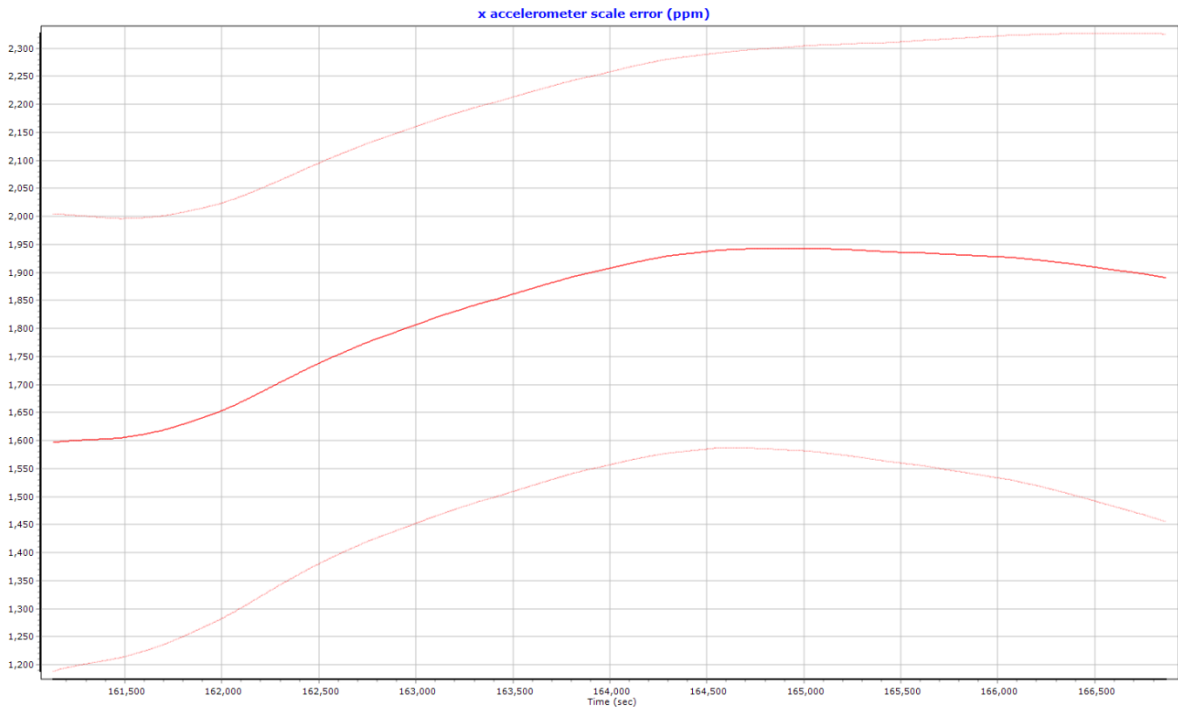
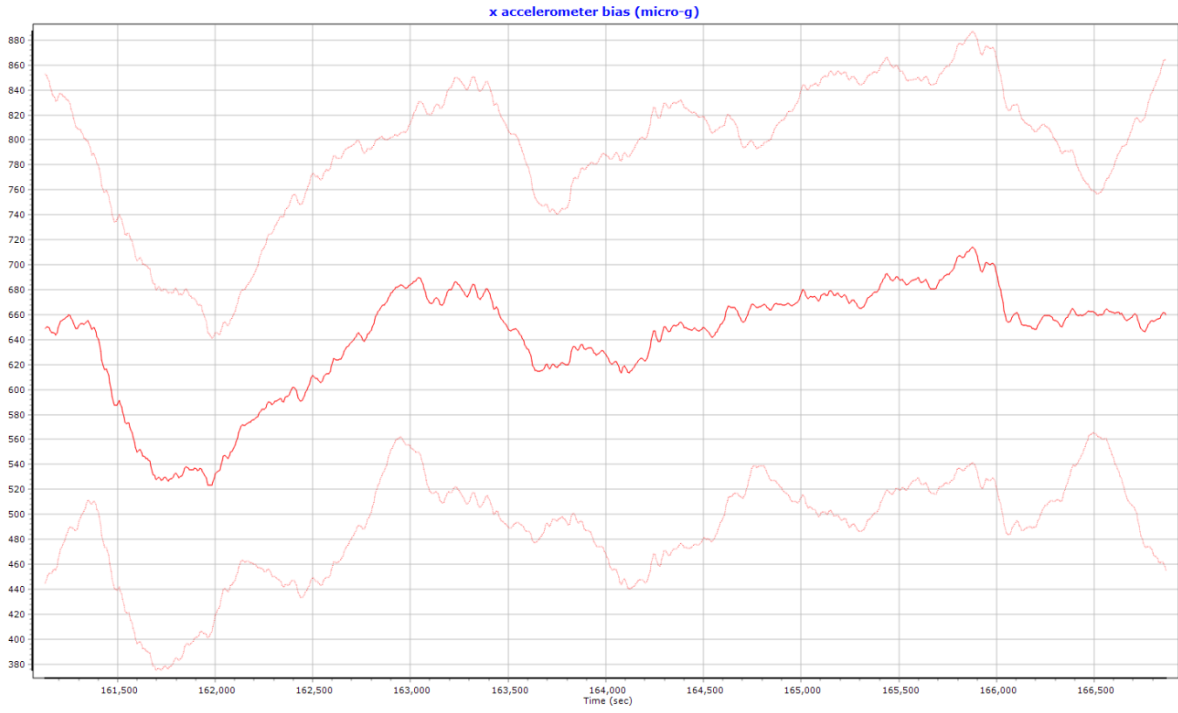
End: 166875.681 Output Record 0.005000

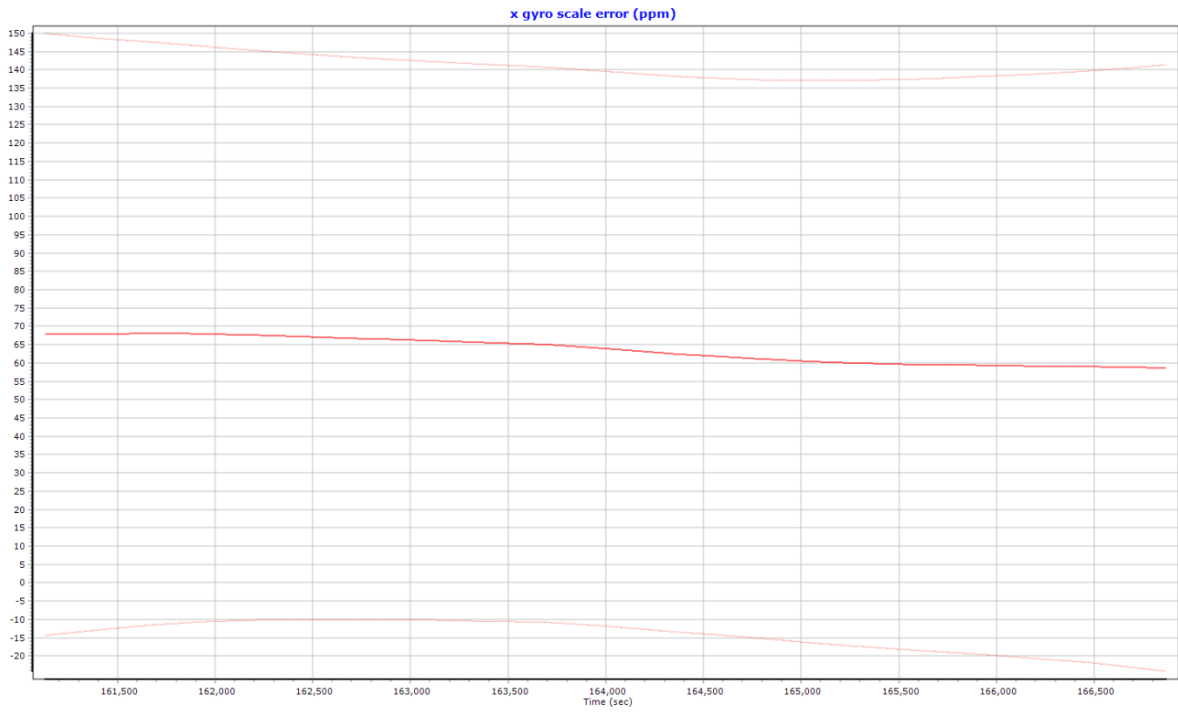
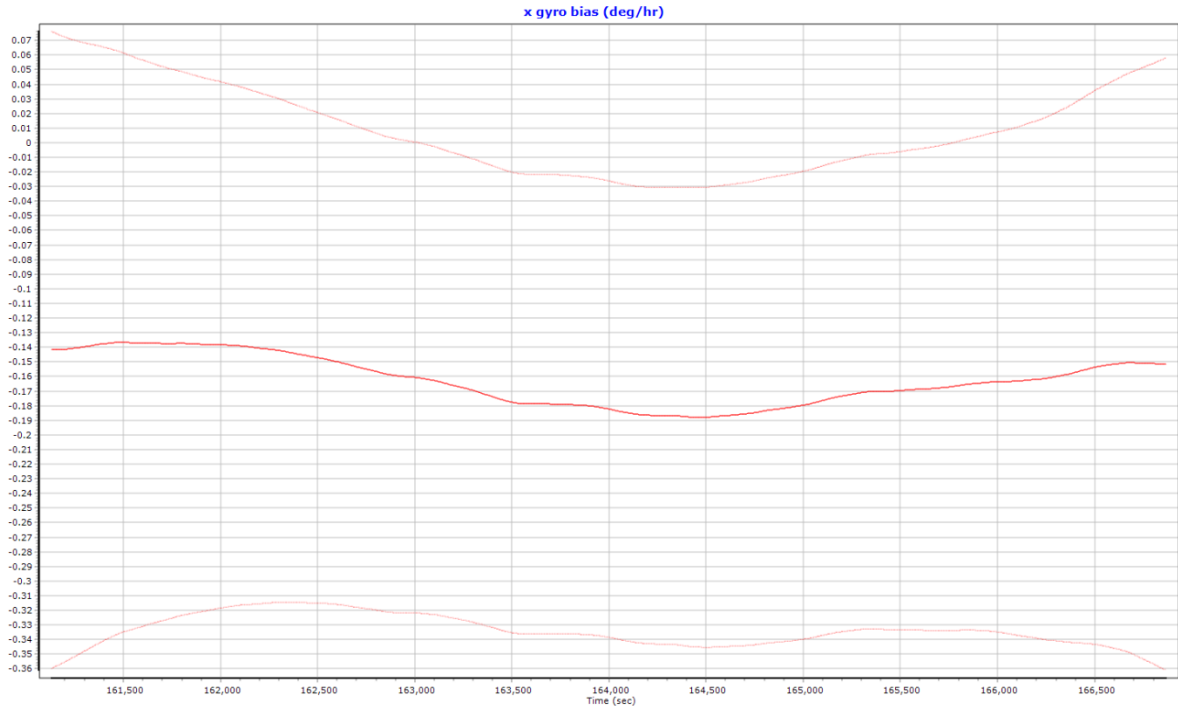
Entire time interval IMU 0.005000

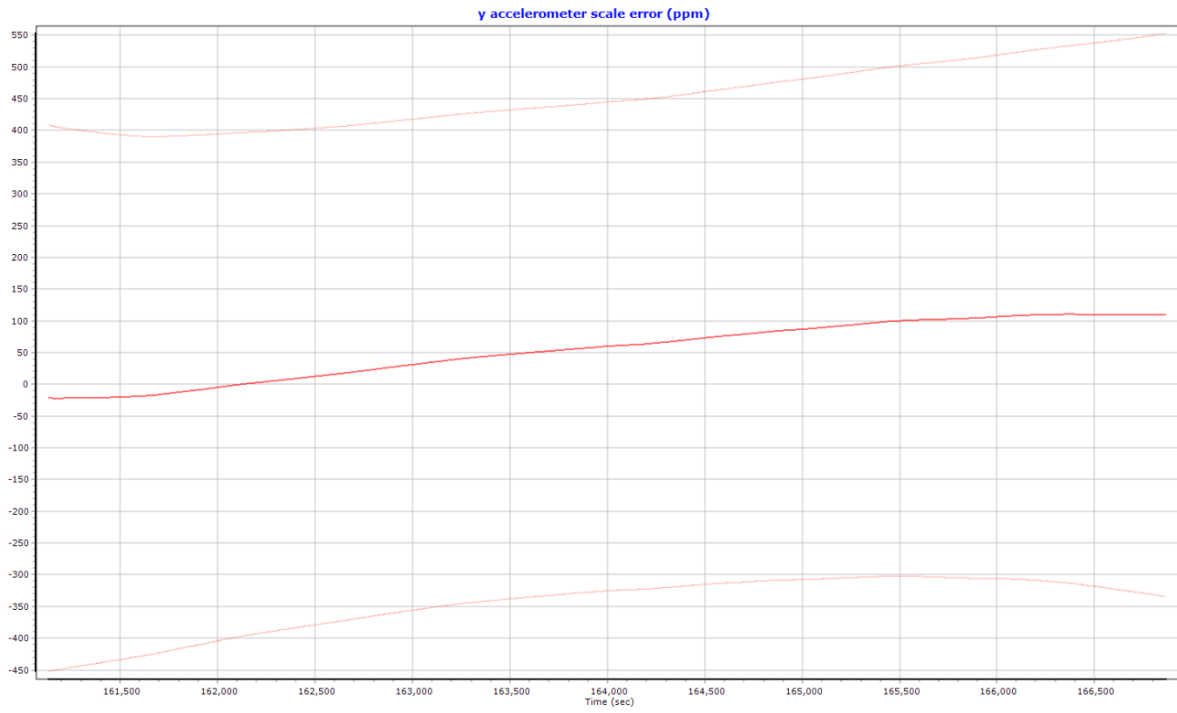
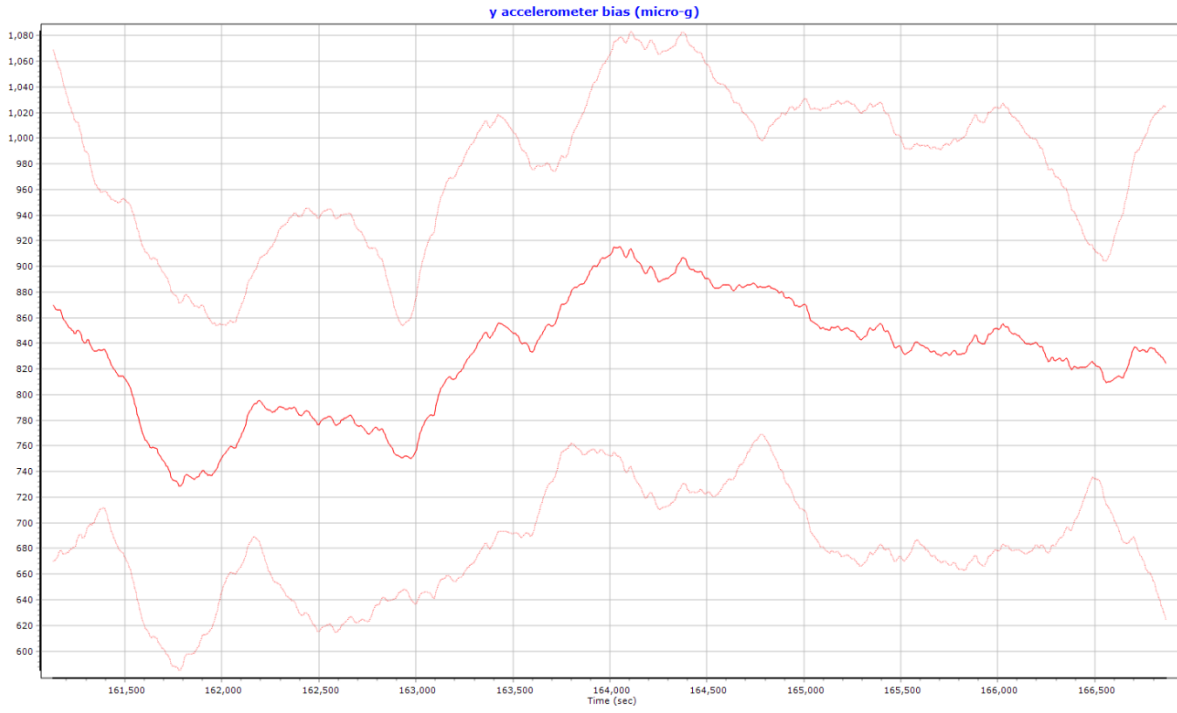
Seconds of start week Primary GNSS 1.000000

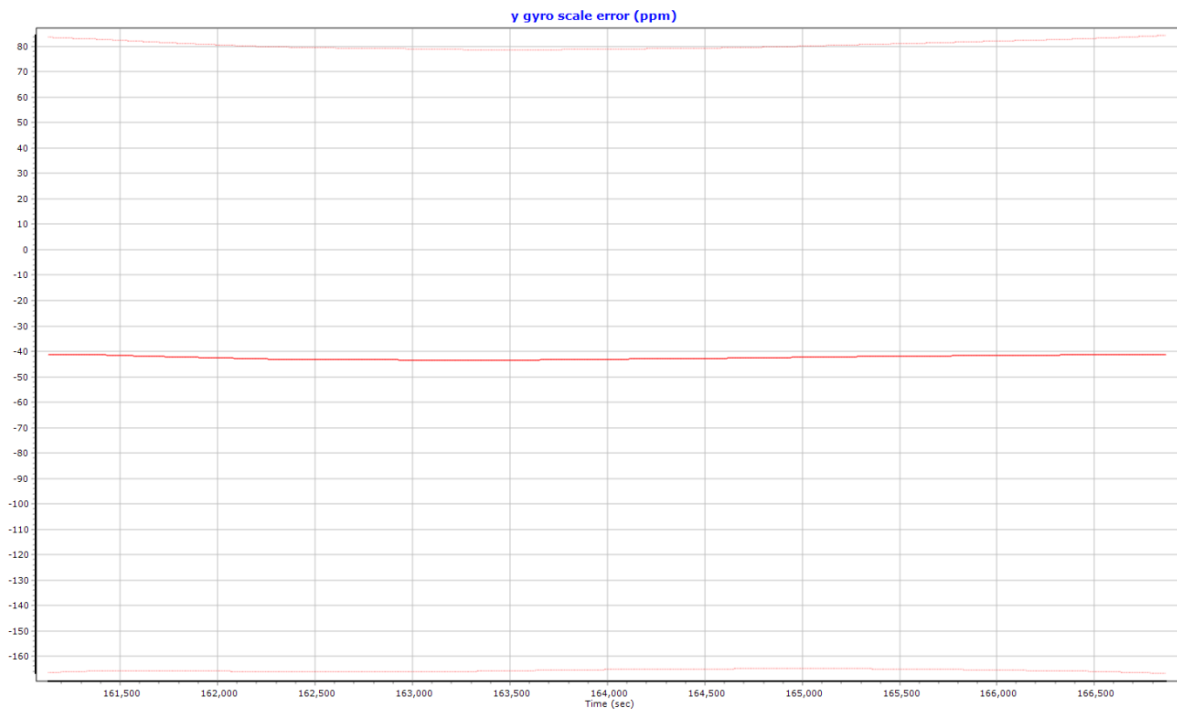
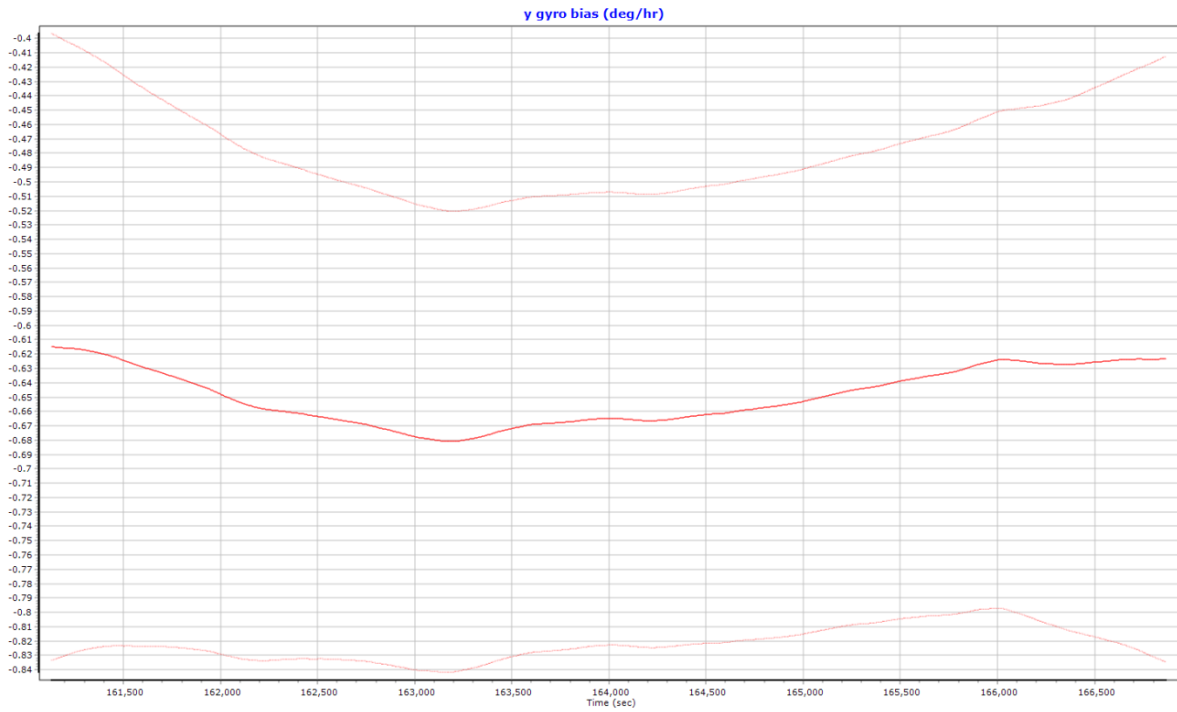
UTC Offset: 18.000

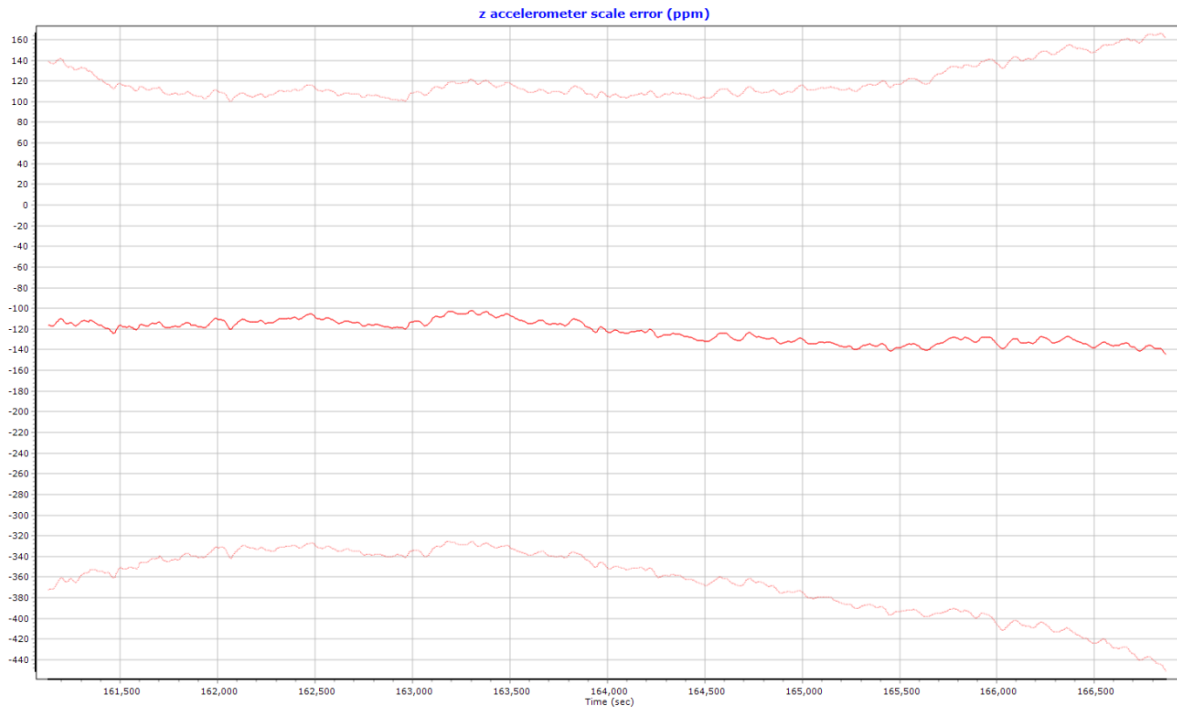
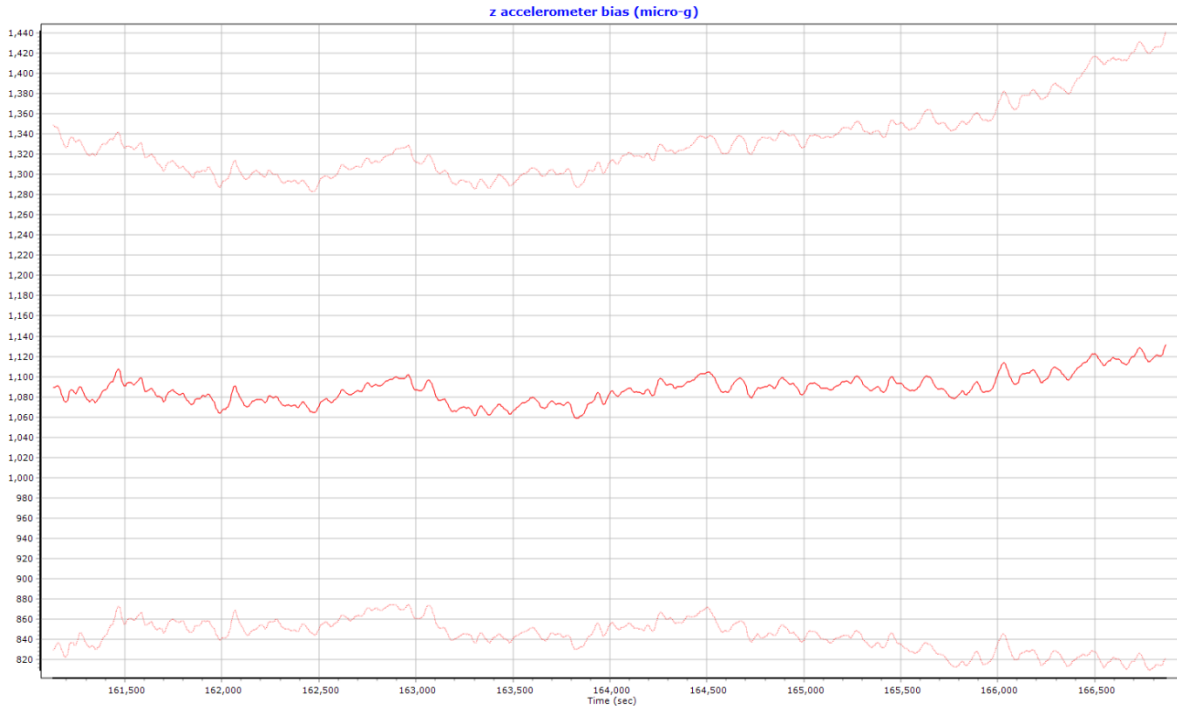
[OK] [Cancel]

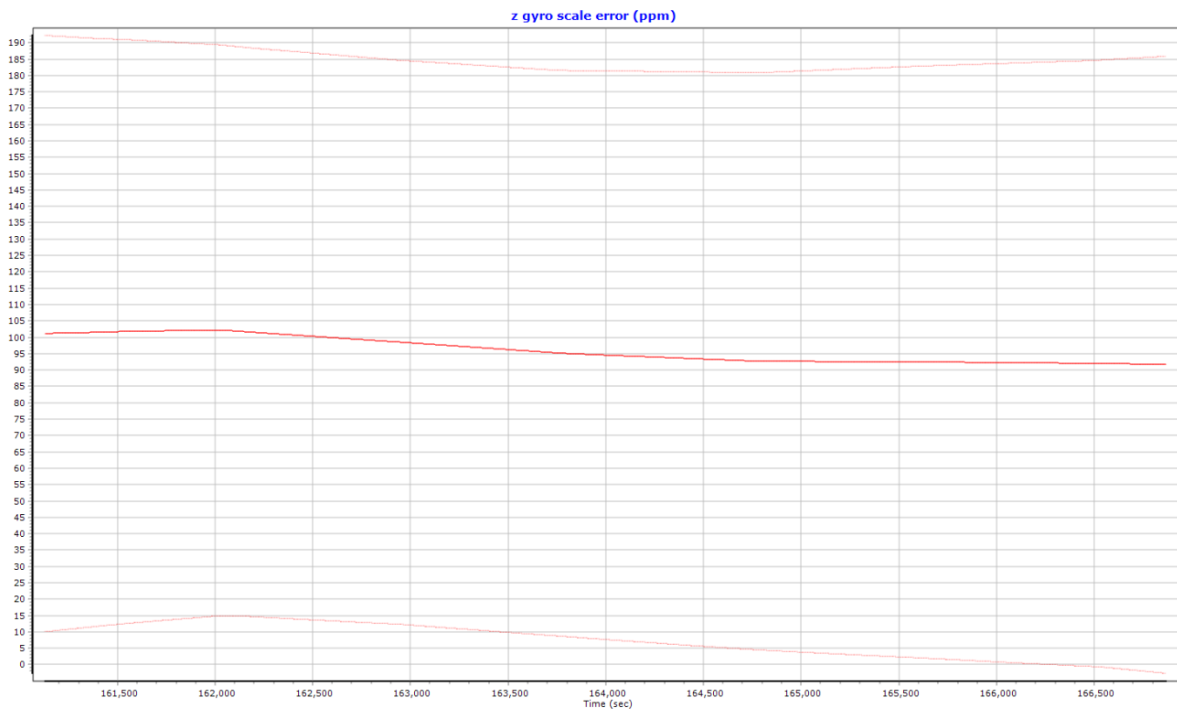
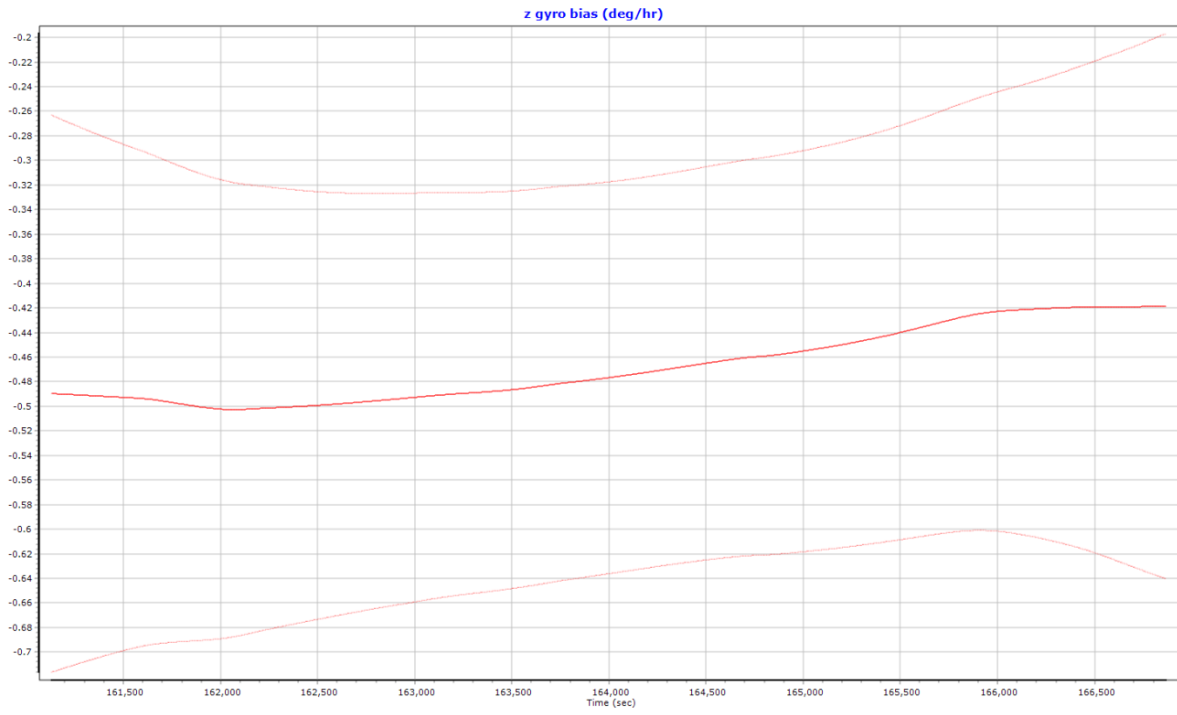




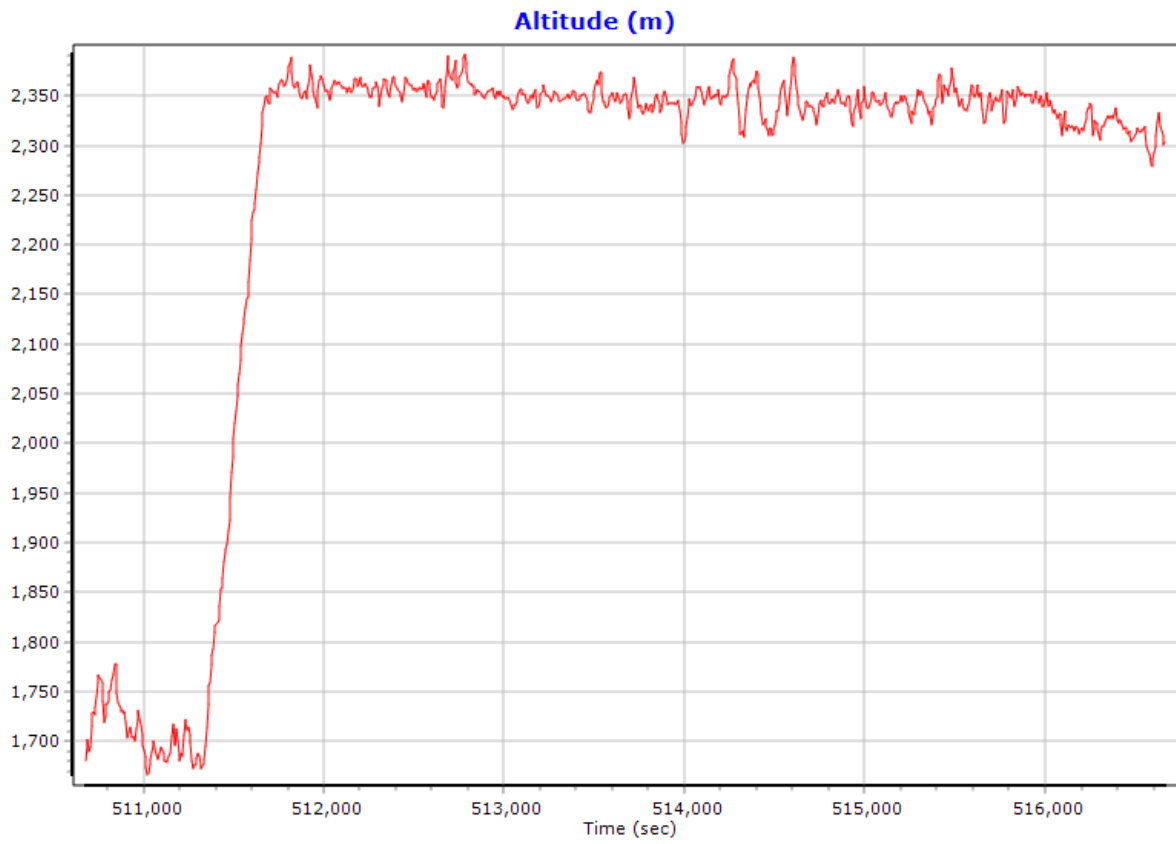


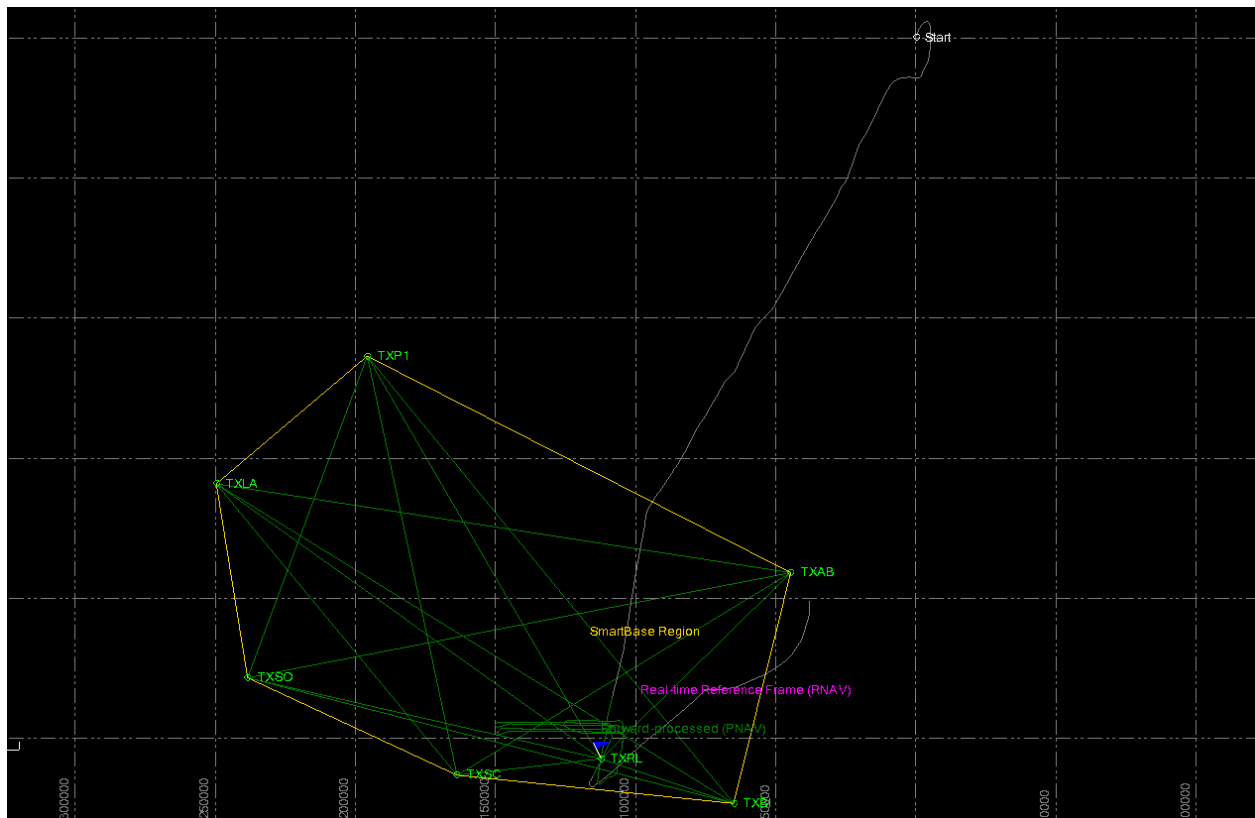
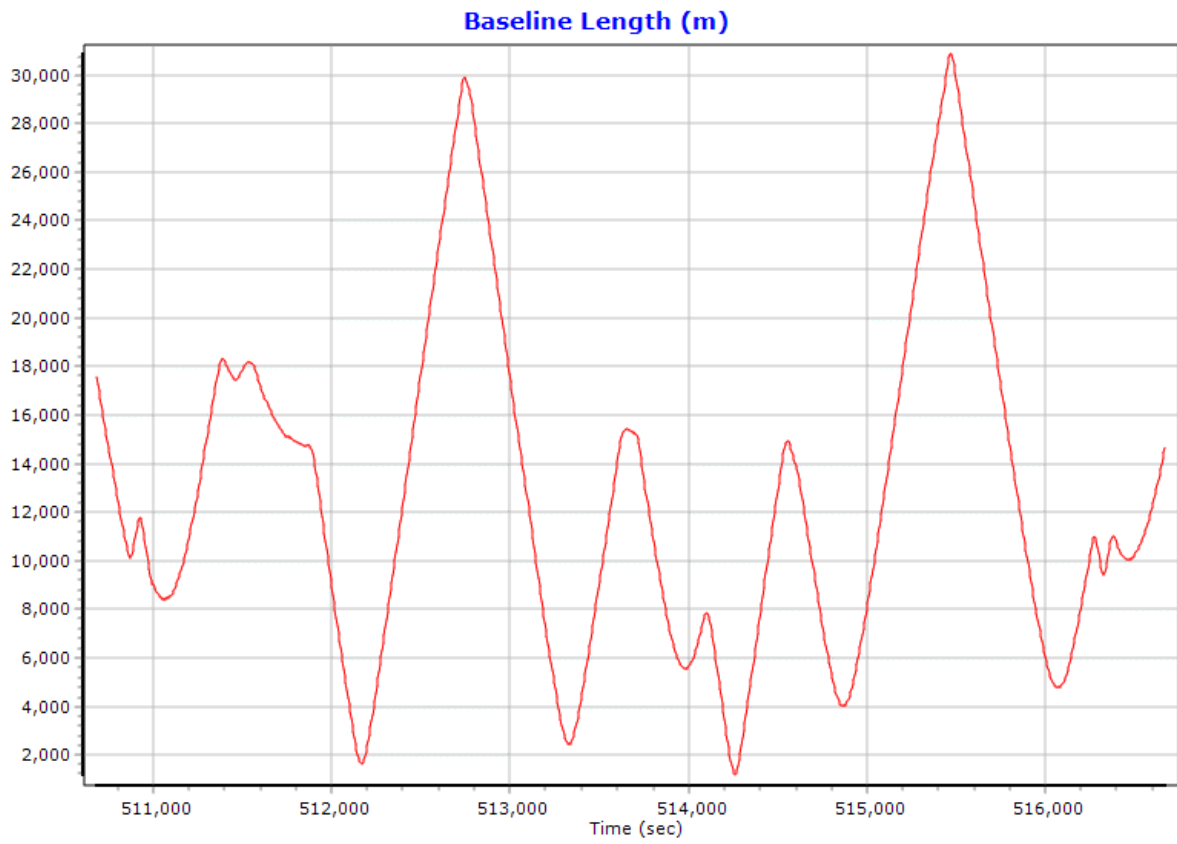


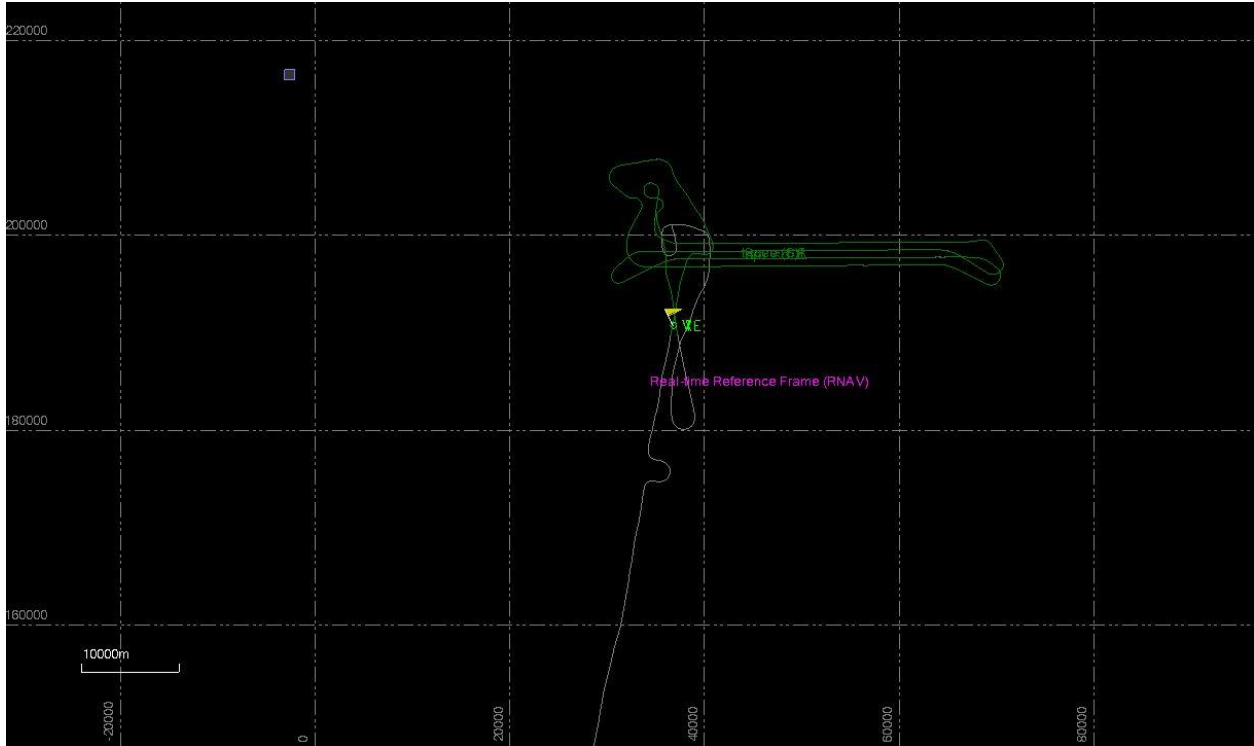




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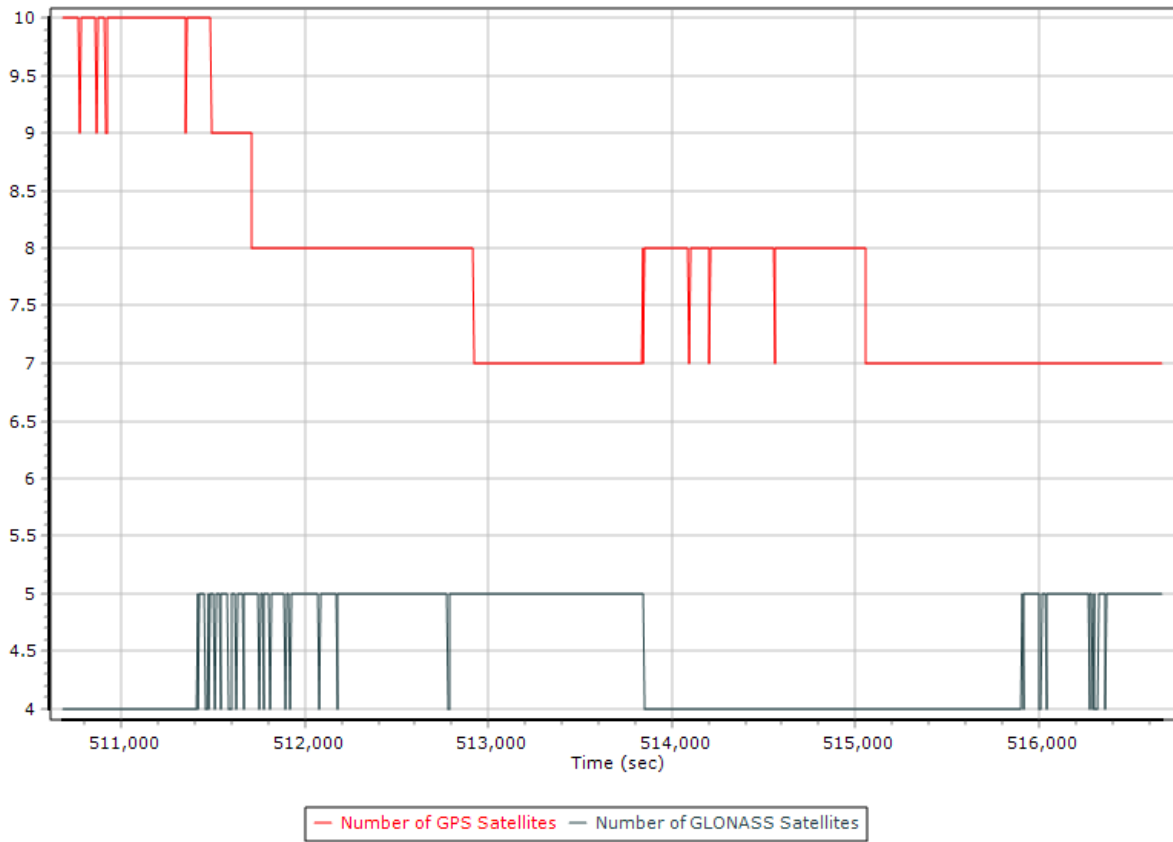
Disable Satellites

GPS GLONASS BEIDOU QZSS

<input type="checkbox"/> SLOT 1	<input type="checkbox"/> SLOT 10	<input type="checkbox"/> SLOT 19
<input type="checkbox"/> SLOT 2	<input type="checkbox"/> SLOT 11	<input type="checkbox"/> SLOT 20
<input type="checkbox"/> SLOT 3	<input type="checkbox"/> SLOT 12	<input type="checkbox"/> SLOT 21
<input type="checkbox"/> SLOT 4	<input type="checkbox"/> SLOT 13	<input type="checkbox"/> SLOT 22
<input type="checkbox"/> SLOT 5	<input type="checkbox"/> SLOT 14	<input type="checkbox"/> SLOT 23
<input type="checkbox"/> SLOT 6	<input type="checkbox"/> SLOT 15	<input type="checkbox"/> SLOT 24
<input type="checkbox"/> SLOT 7	<input type="checkbox"/> SLOT 16	
<input type="checkbox"/> SLOT 8	<input type="checkbox"/> SLOT 17	
<input type="checkbox"/> SLOT 9	<input type="checkbox"/> SLOT 18	

Elevation Mask Angle

Force GPS Only



Disable Satellites

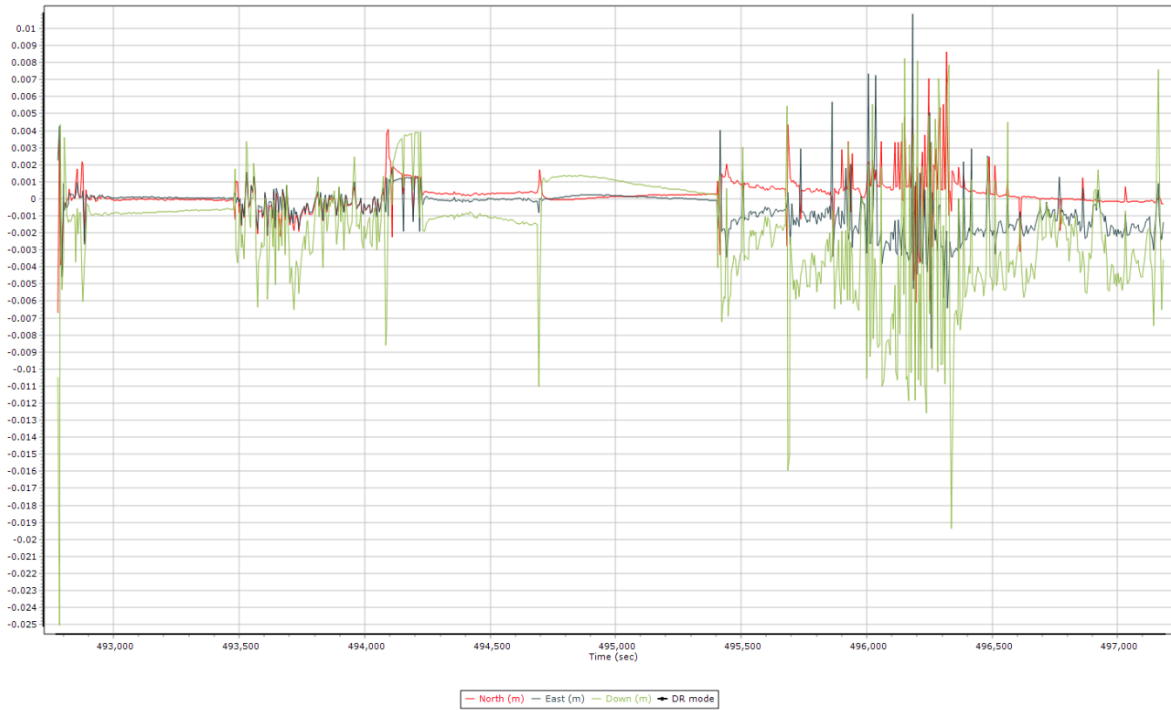
GPS | **GLONASS** | BEIDOU | QZSS

<input type="checkbox"/> PRN 1	<input type="checkbox"/> PRN 10	<input type="checkbox"/> PRN 19	<input type="checkbox"/> PR
<input type="checkbox"/> PRN 2	<input type="checkbox"/> PRN 11	<input type="checkbox"/> PRN 20	<input type="checkbox"/> PR
<input type="checkbox"/> PRN 3	<input type="checkbox"/> PRN 12	<input type="checkbox"/> PRN 21	<input type="checkbox"/> PR
<input type="checkbox"/> PRN 4	<input type="checkbox"/> PRN 13	<input type="checkbox"/> PRN 22	<input type="checkbox"/> PR
<input type="checkbox"/> PRN 5	<input type="checkbox"/> PRN 14	<input type="checkbox"/> PRN 23	<input type="checkbox"/> PR
<input type="checkbox"/> PRN 6	<input type="checkbox"/> PRN 15	<input type="checkbox"/> PRN 24	
<input type="checkbox"/> PRN 7	<input type="checkbox"/> PRN 16	<input type="checkbox"/> PRN 25	
<input type="checkbox"/> PRN 8	<input type="checkbox"/> PRN 17	<input type="checkbox"/> PRN 26	
<input type="checkbox"/> PRN 9	<input type="checkbox"/> PRN 18	<input type="checkbox"/> PRN 27	

< [Progress Bar] >

Elevation Mask Angle:

Force GPS Only



Project Settings

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

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

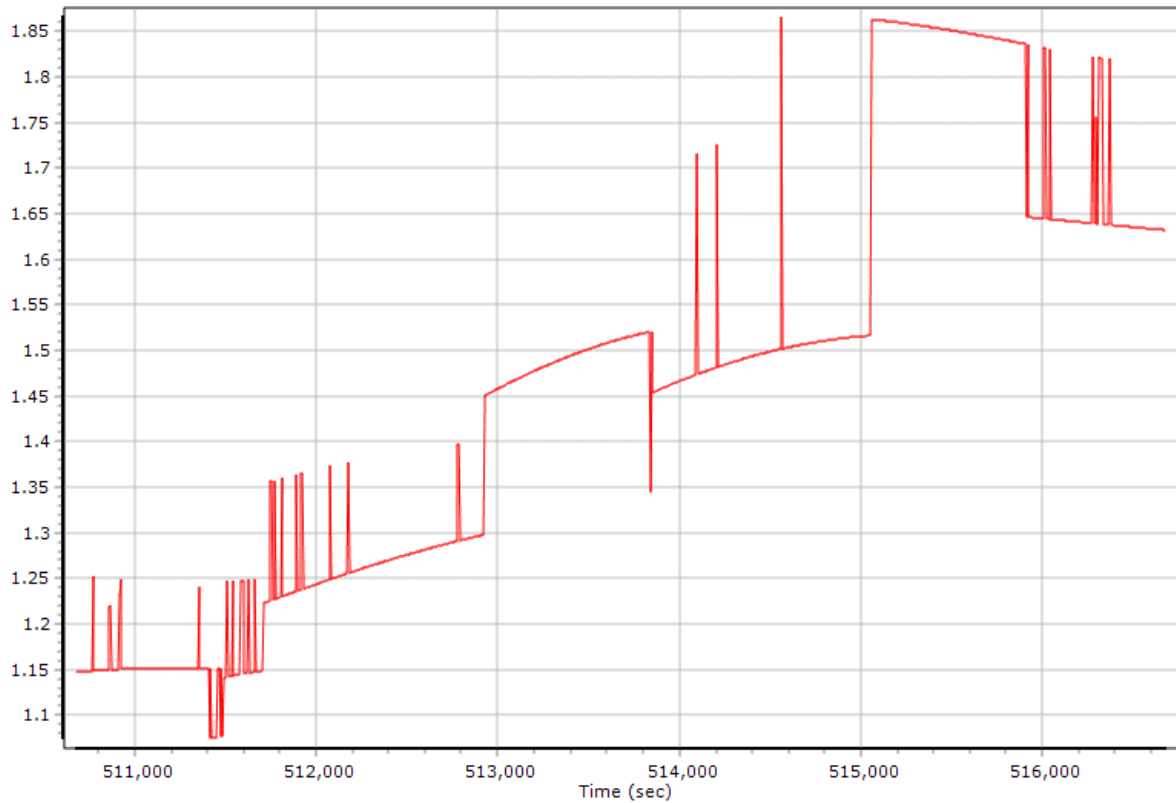
Reference to Primary GNSS Lever Arm	Aircraft to Reference Mounting Angles
X: -0.105 m	X: 0.000 deg
Y: -0.052 m	Y: 0.000 deg
Z: -0.964 m	Z: 0.000 deg

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

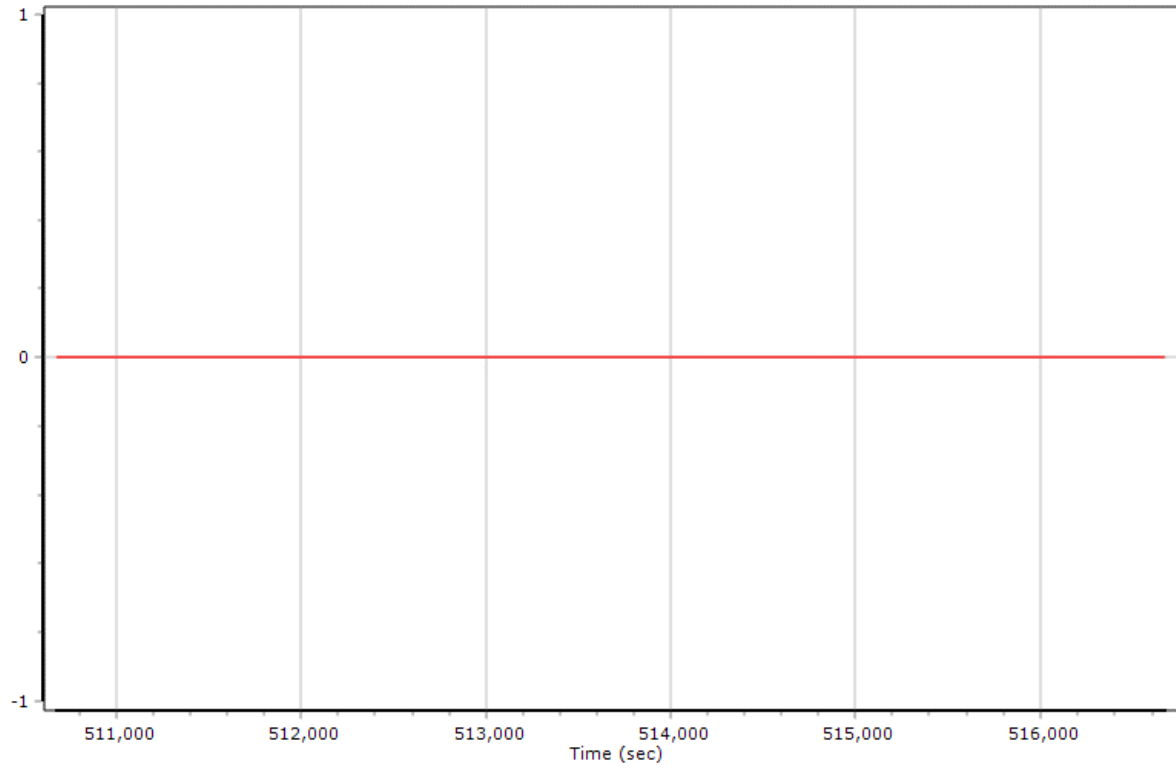
OK Cancel

Reference to IMU Lever Arm		Reference to IMU Mounting Angles	
X	<input type="text" value="0.034 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="0.018 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.155 m"/>	Z	<input type="text" value="0.000 deg"/>
Reference to Primary GNSS Lever Arm		Aircraft to Reference Mounting Angles	
X	<input type="text" value="-0.105 m"/>	X	<input type="text" value="0.000 deg"/>
Y	<input type="text" value="-0.052 m"/>	Y	<input type="text" value="0.000 deg"/>
Z	<input type="text" value="-0.964 m"/>	Z	<input type="text" value="0.000 deg"/>
Standard Deviation	<input type="range" value="3cm"/> <input type="text" value="3cm"/> <input type="text" value="10cm"/> <input type="text" value="50cm"/> <input type="text" value="1m"/> <input type="text" value="10m"/>		

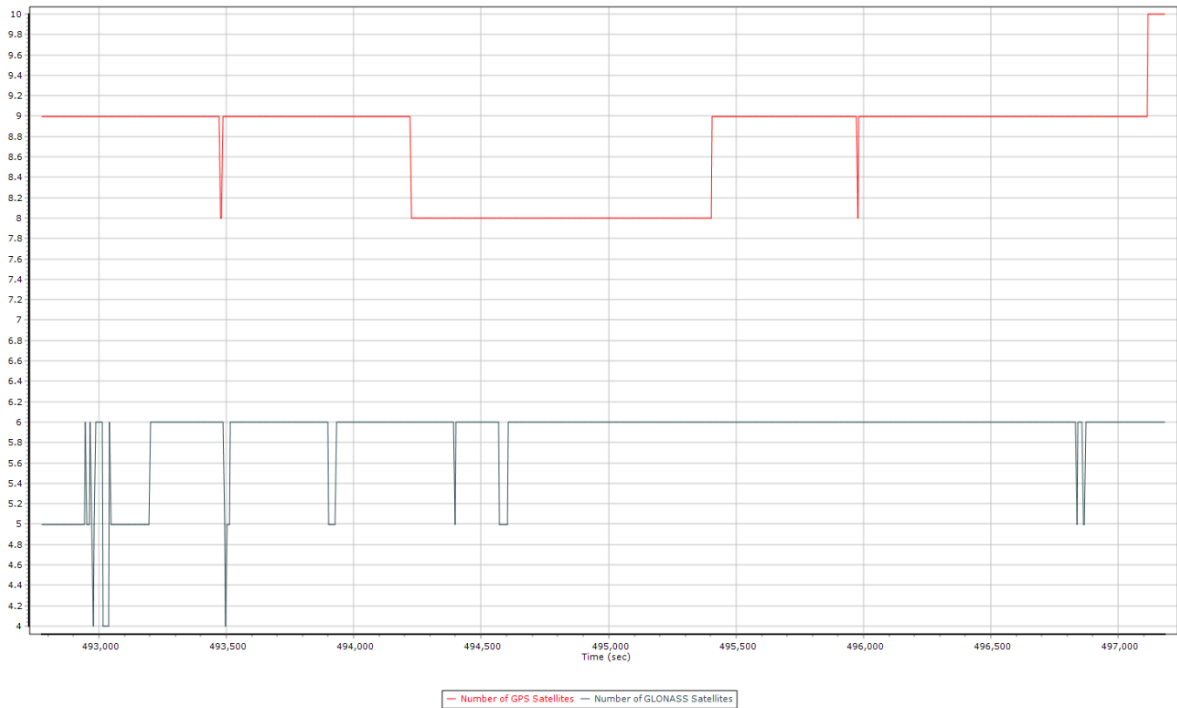
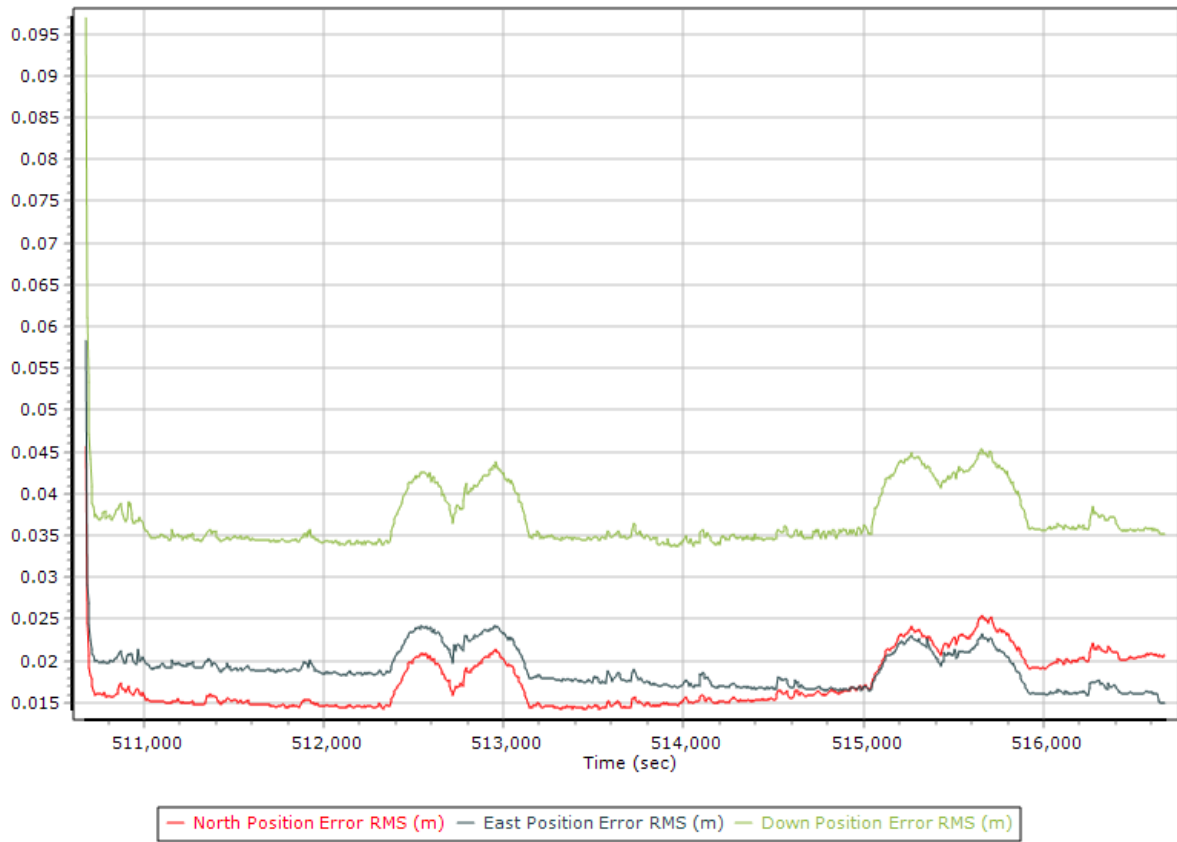
PDOP



Processing mode



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





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

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

Timing

Start: 492774.416
 End: 497186.583
 Entire time interval
 Seconds of start week
 UTC Offset: 18,000

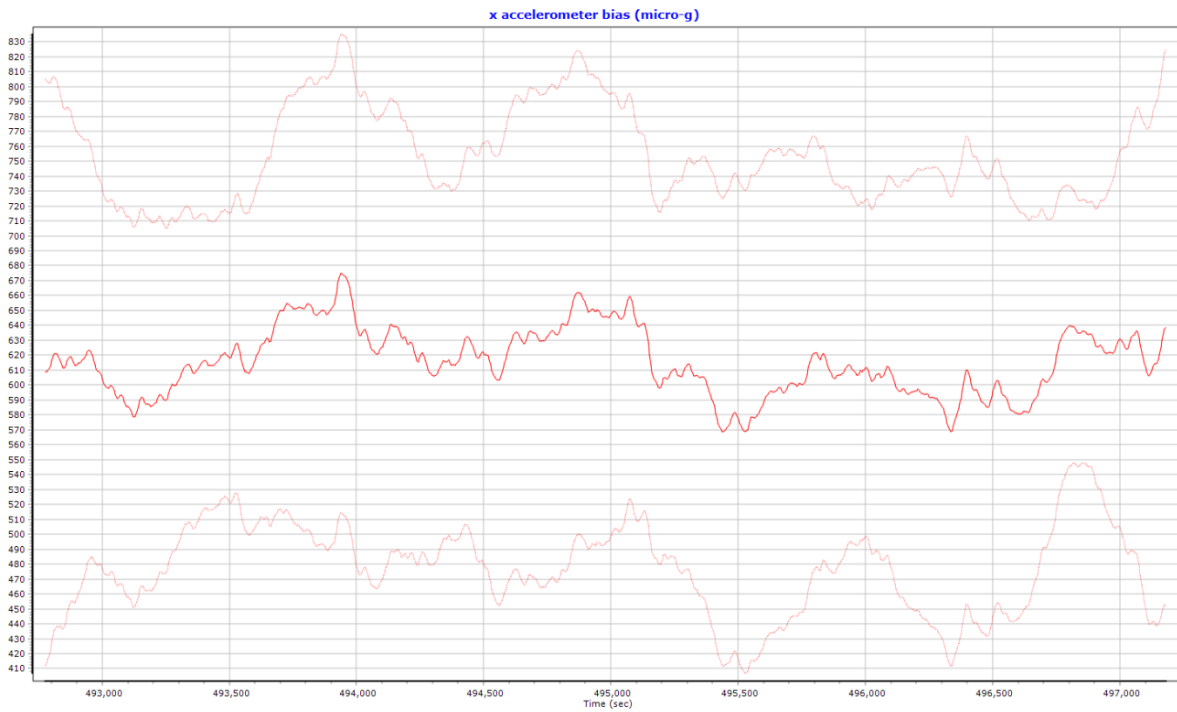
Data	Incr. (sec)
Output Record	0.005000
IMU	0.005000
Primary GNSS	1.000000

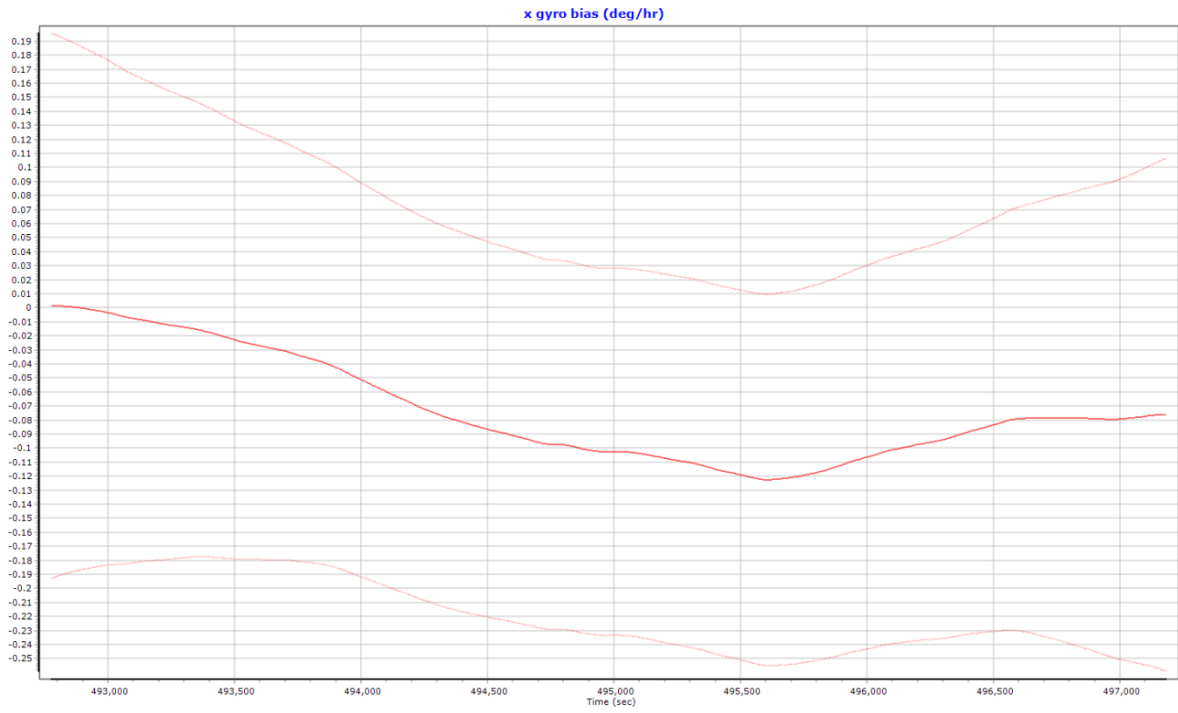
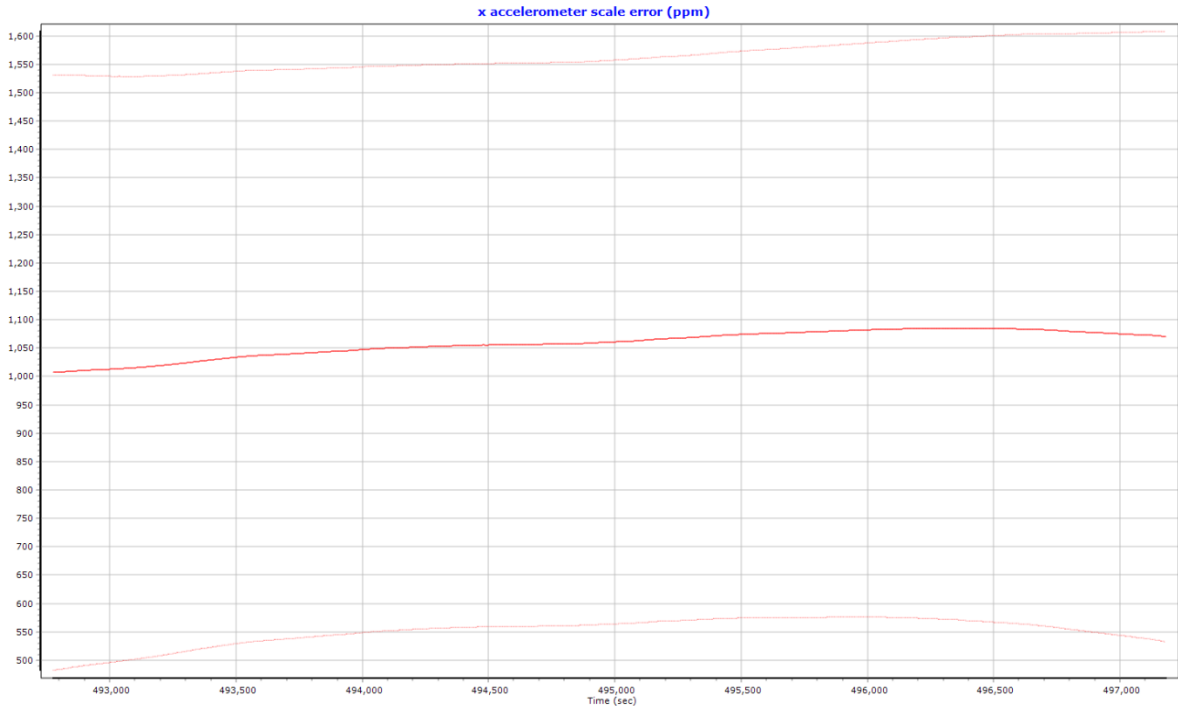
OK Cancel

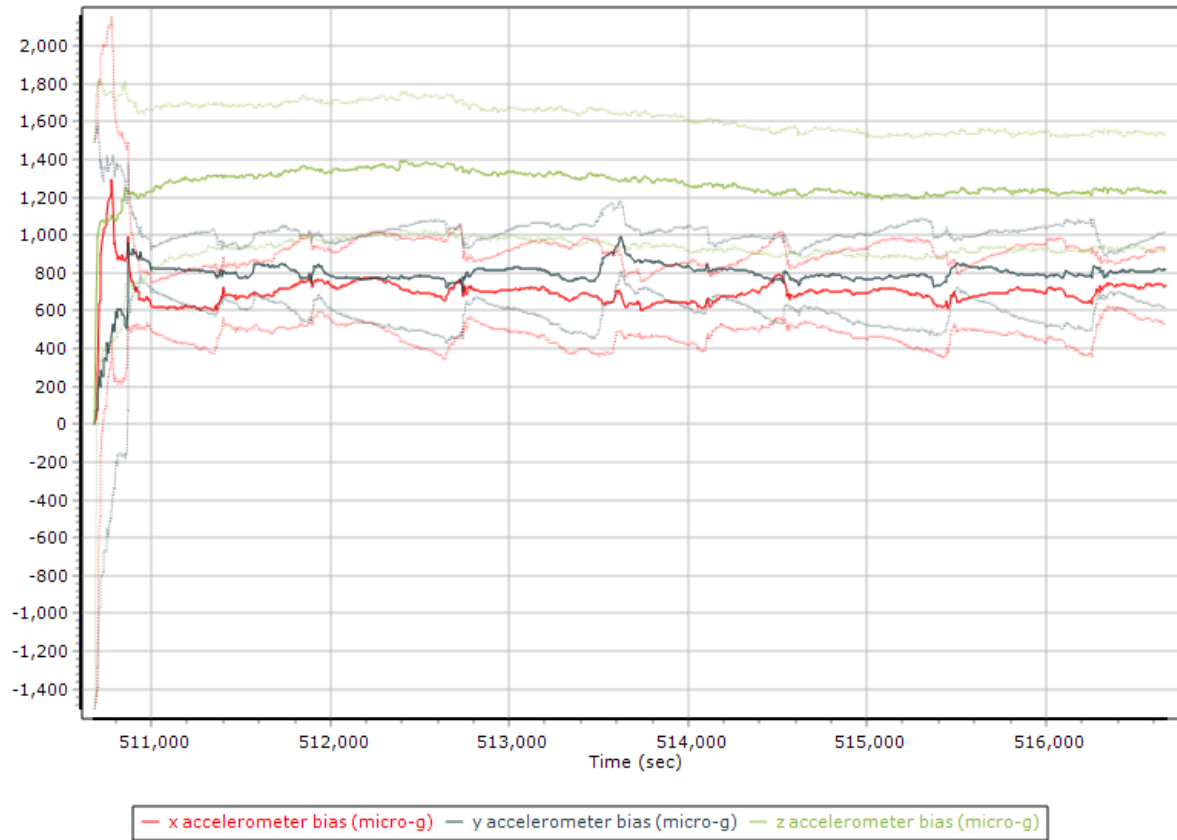
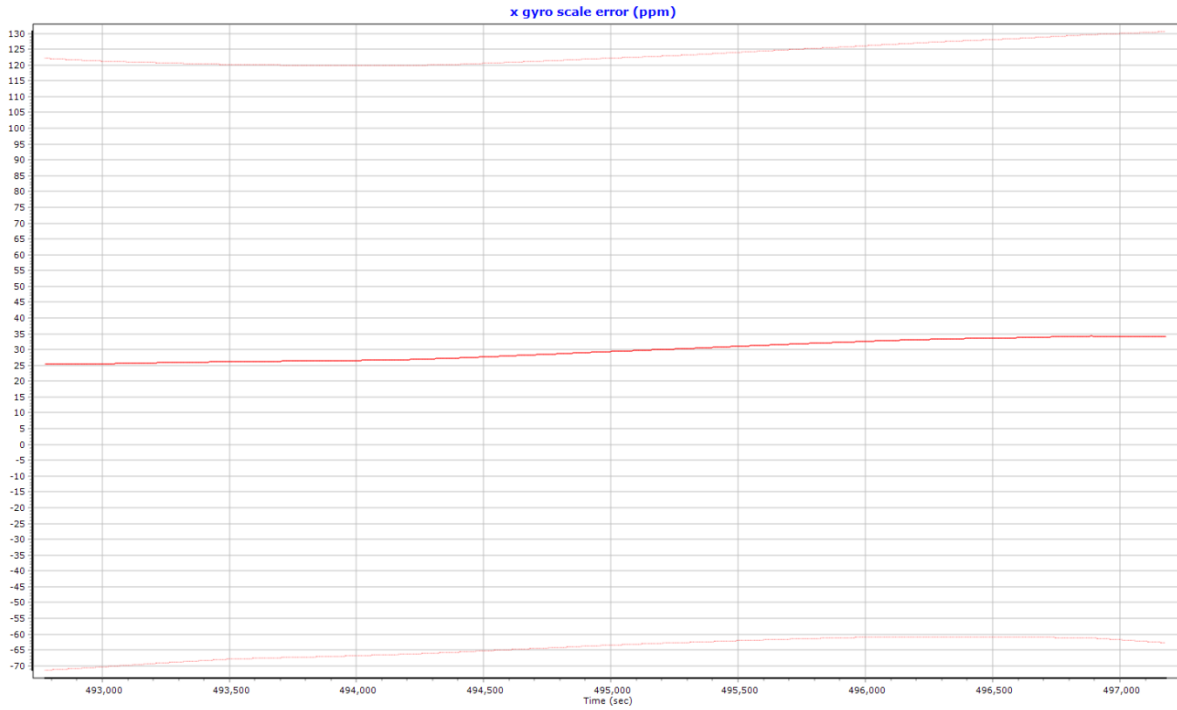
Timing

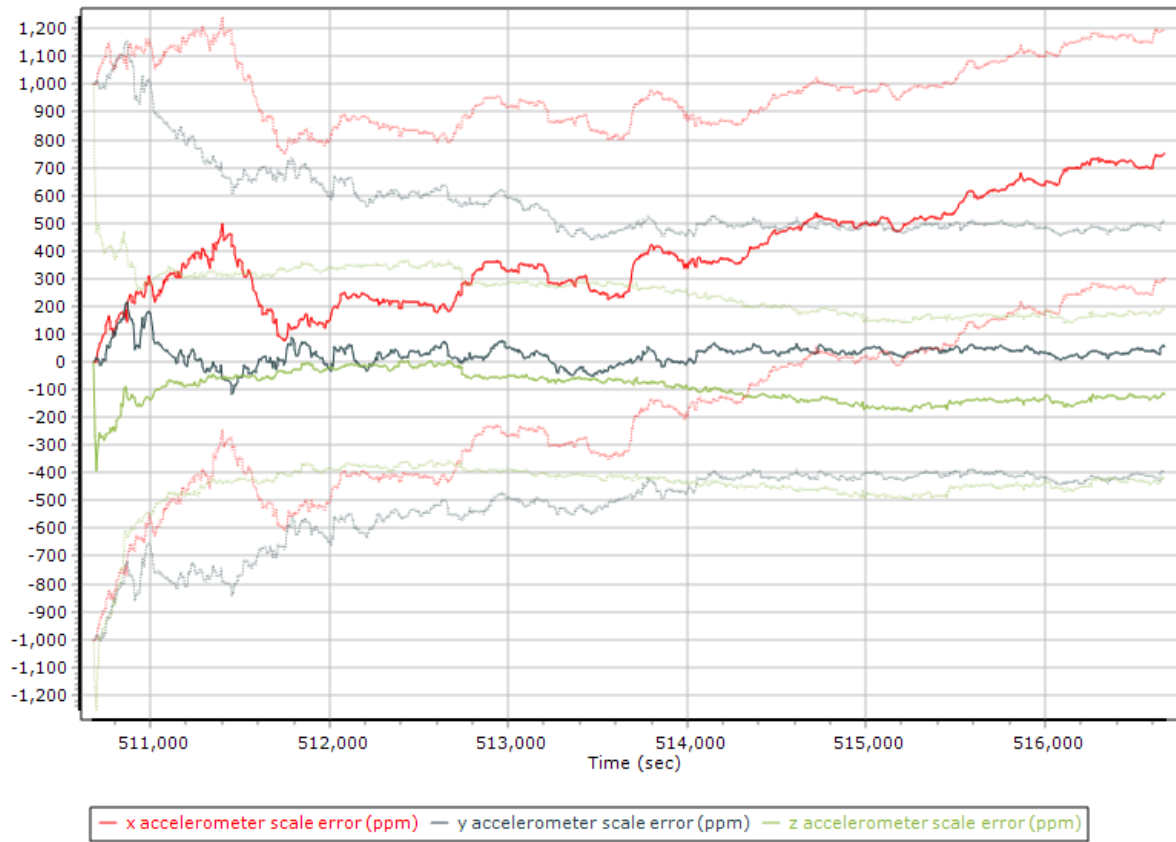
Start	510677.516	Data	Incr. (sec)
End	516679.078	Output Record	0.005000
<input type="checkbox"/> Entire time interval		IMU	0.005000
<input checked="" type="checkbox"/> Seconds of start week		Primary GNSS	1.000000

UTC Offset

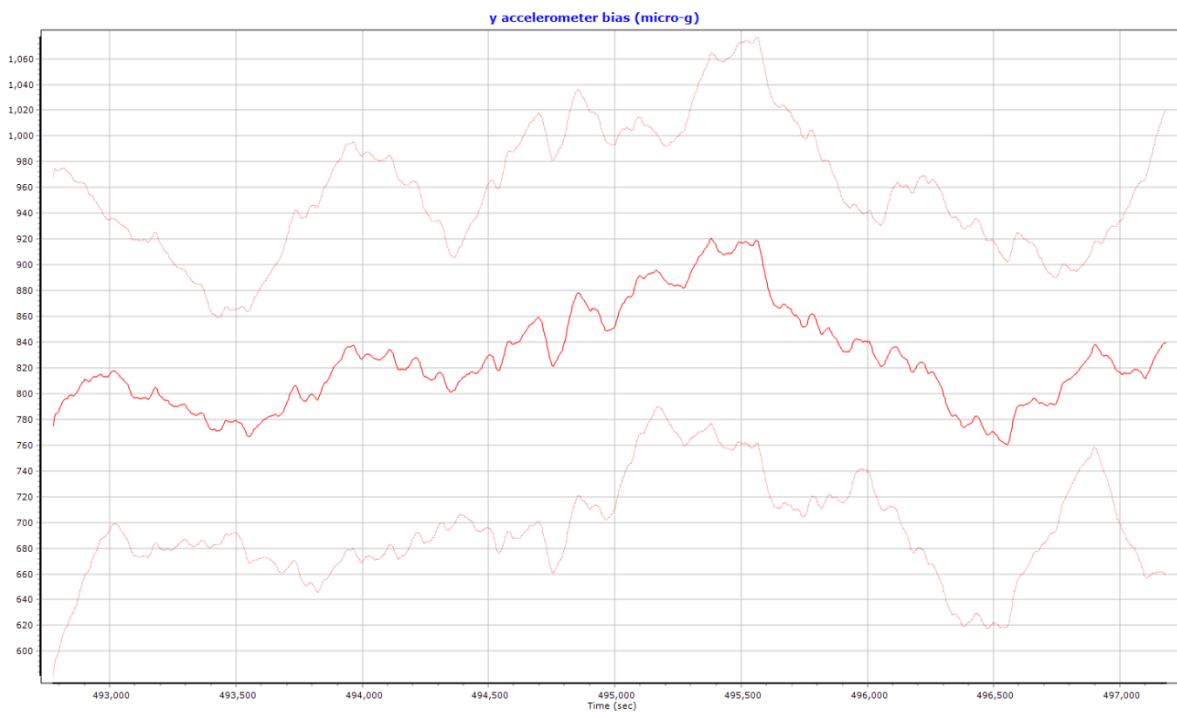
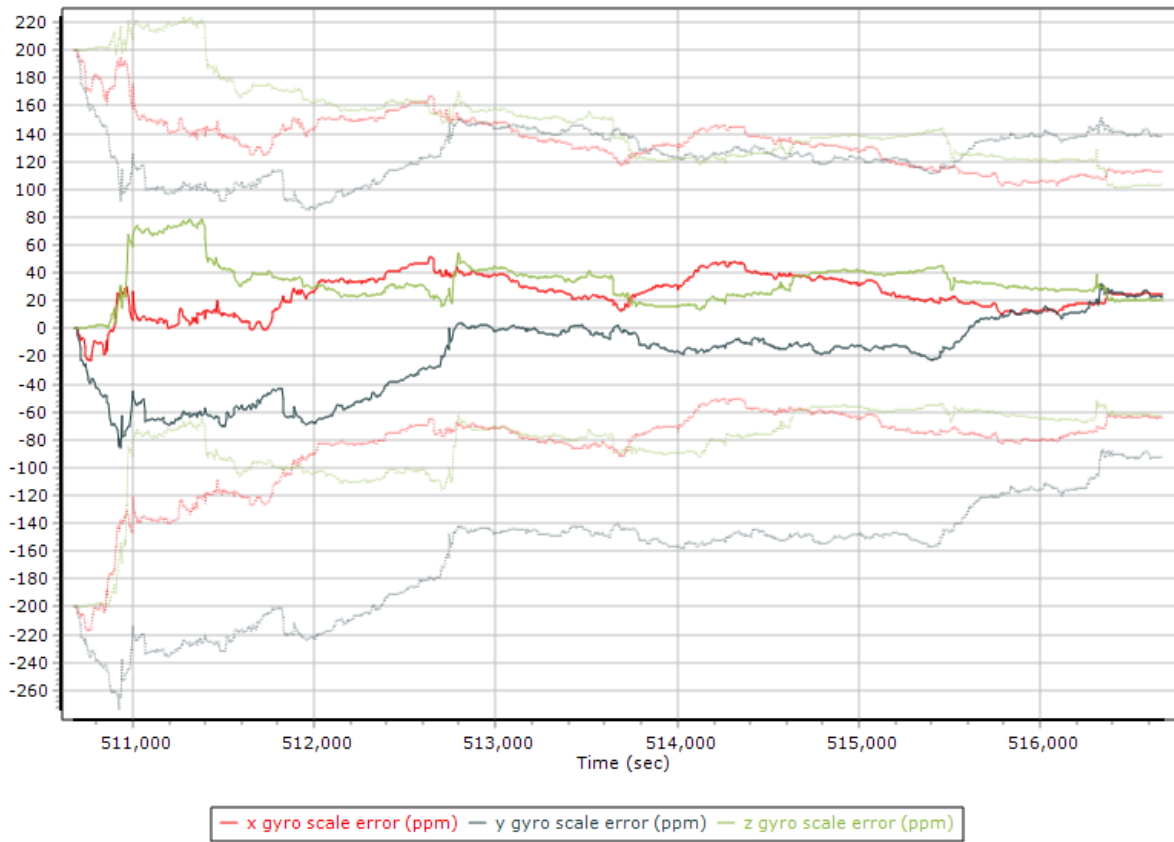


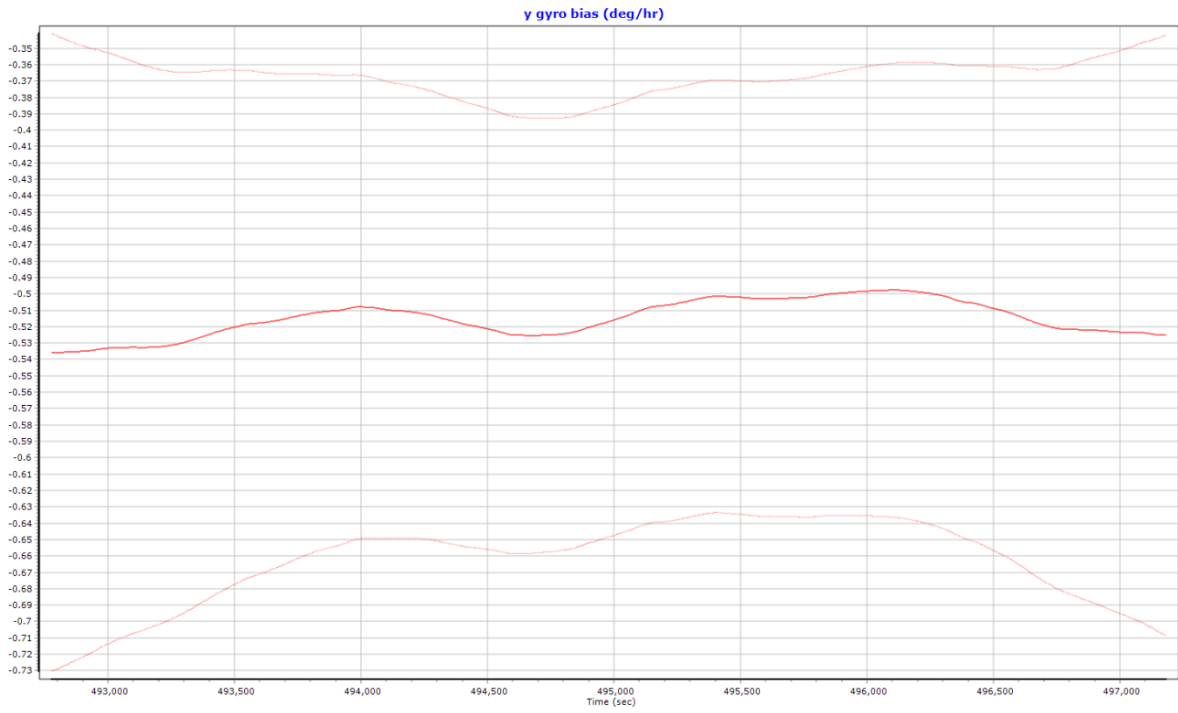
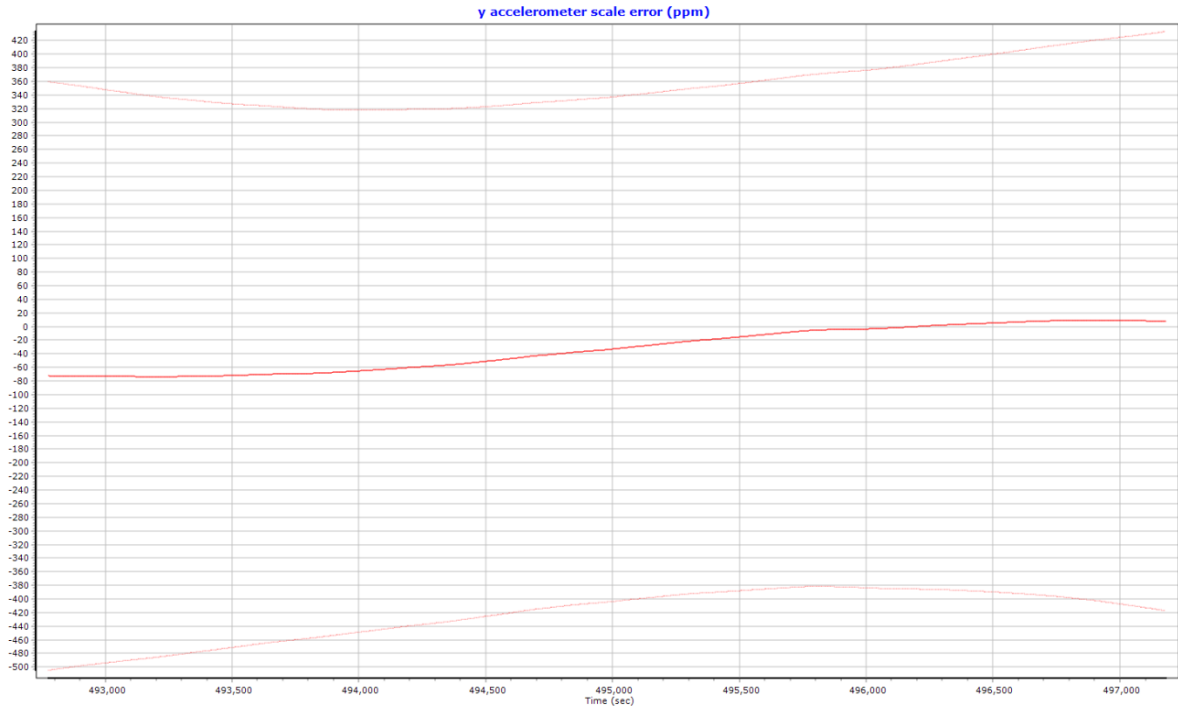


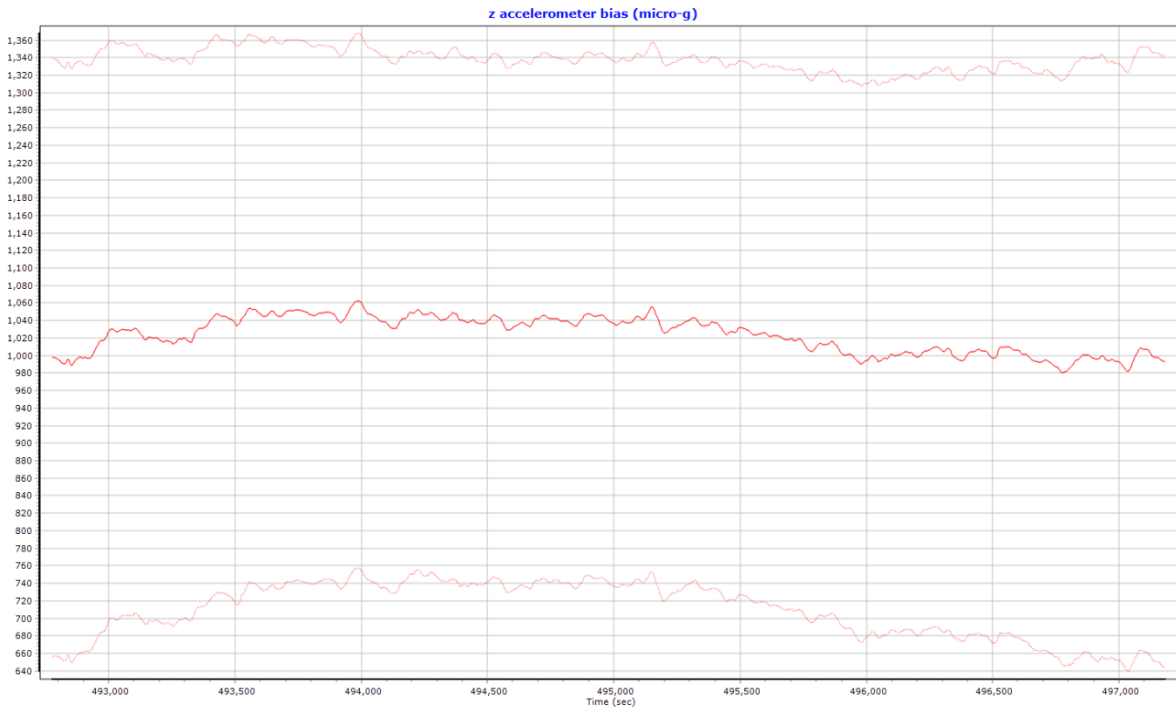
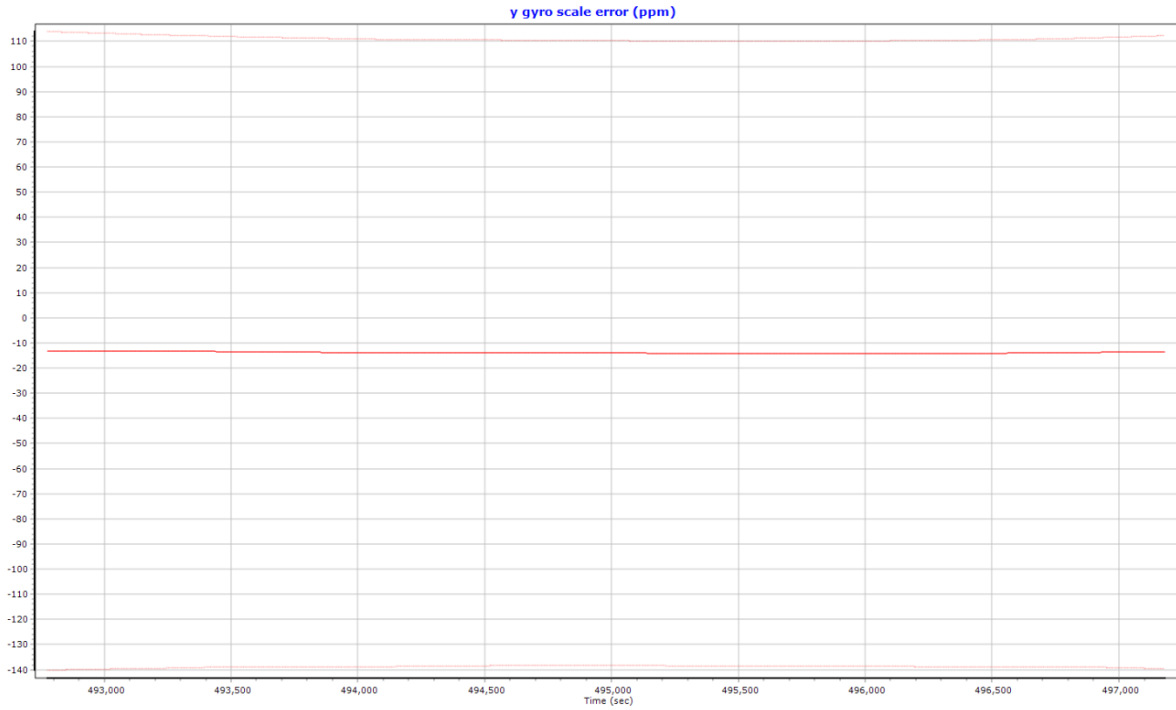


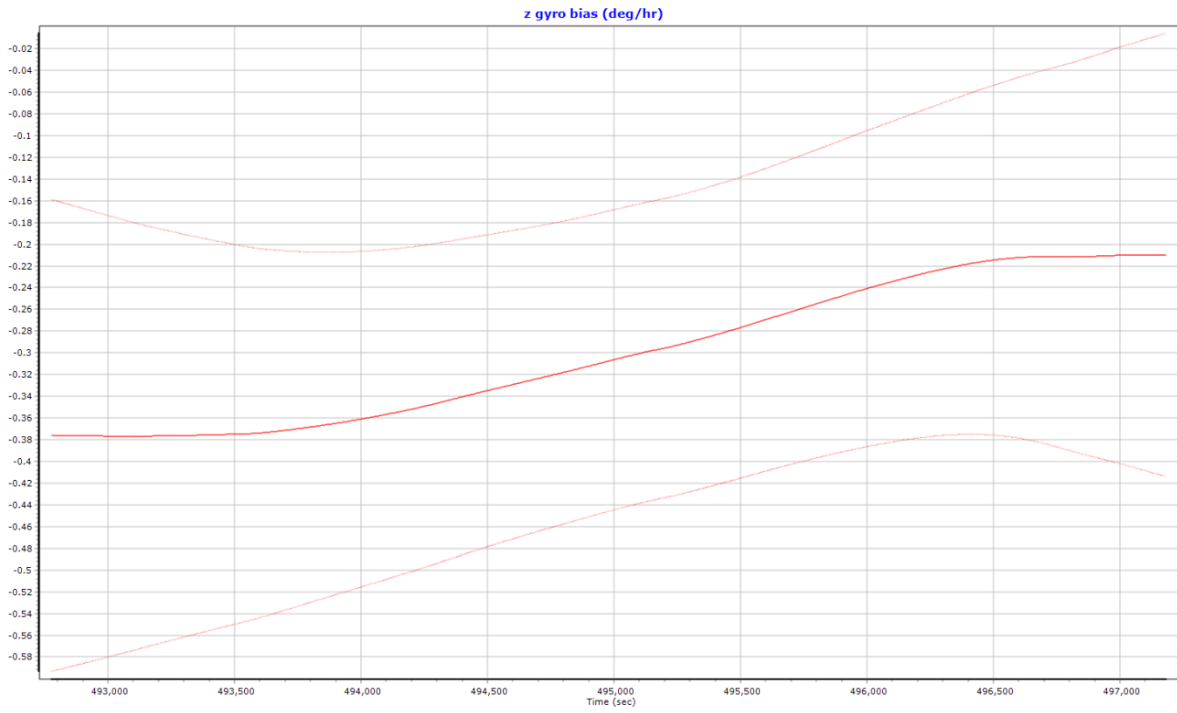
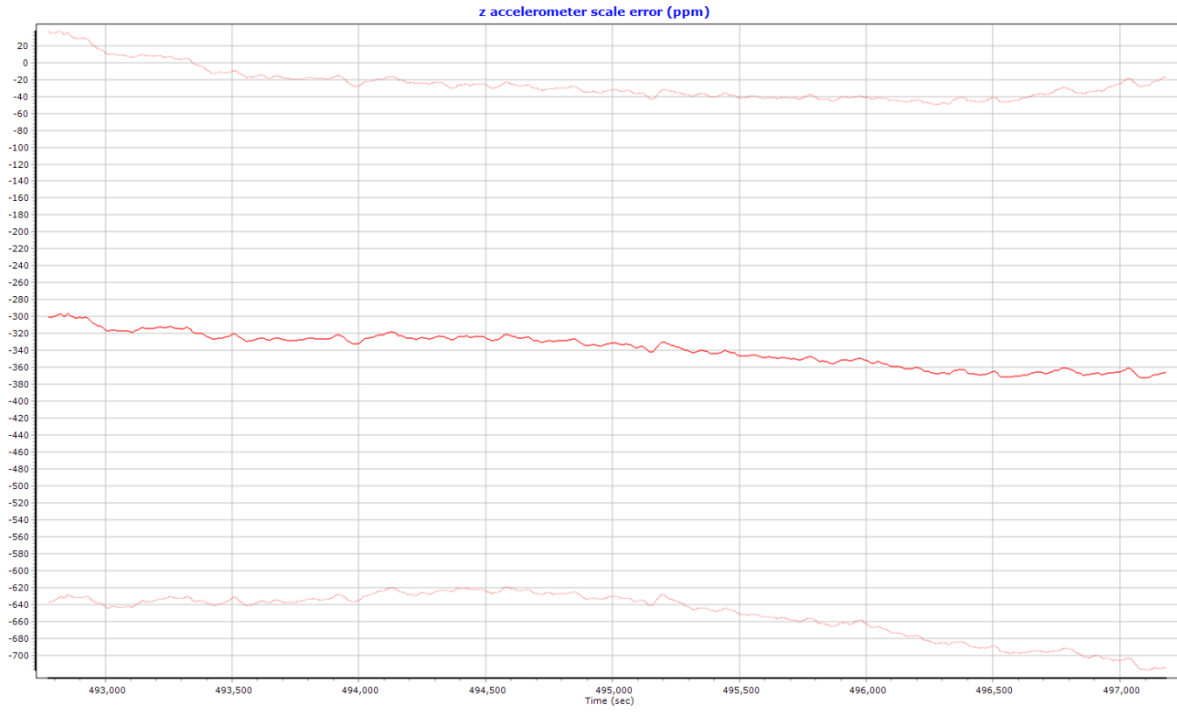


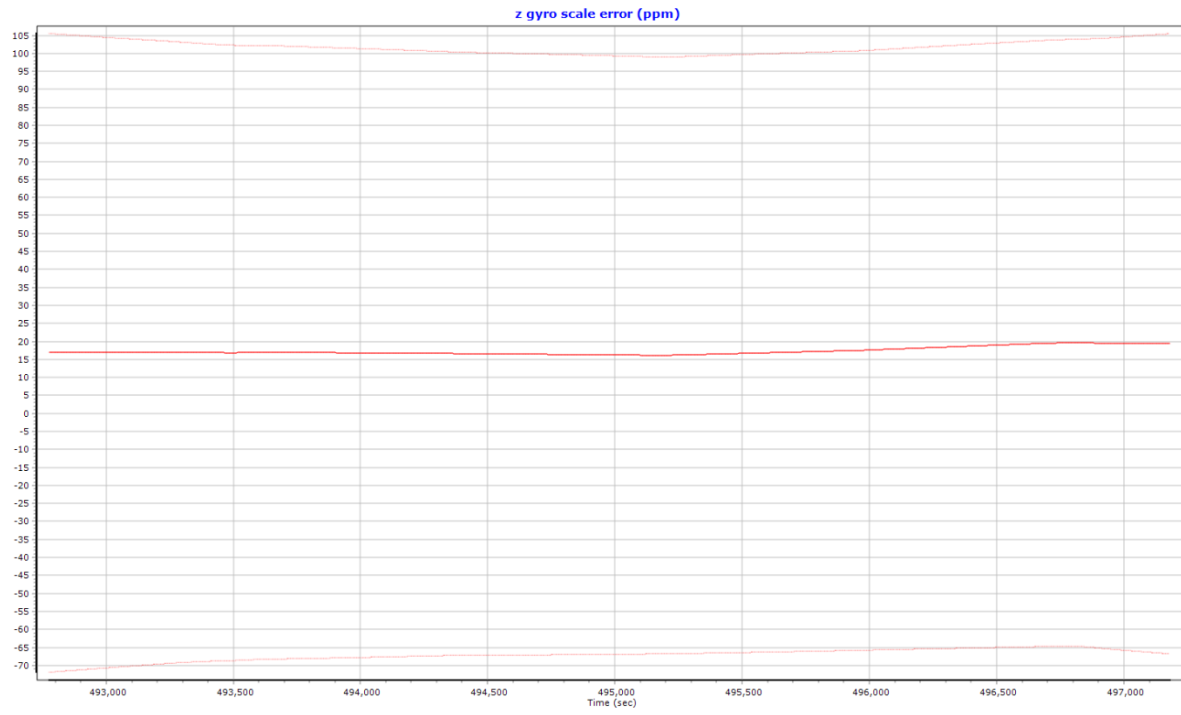




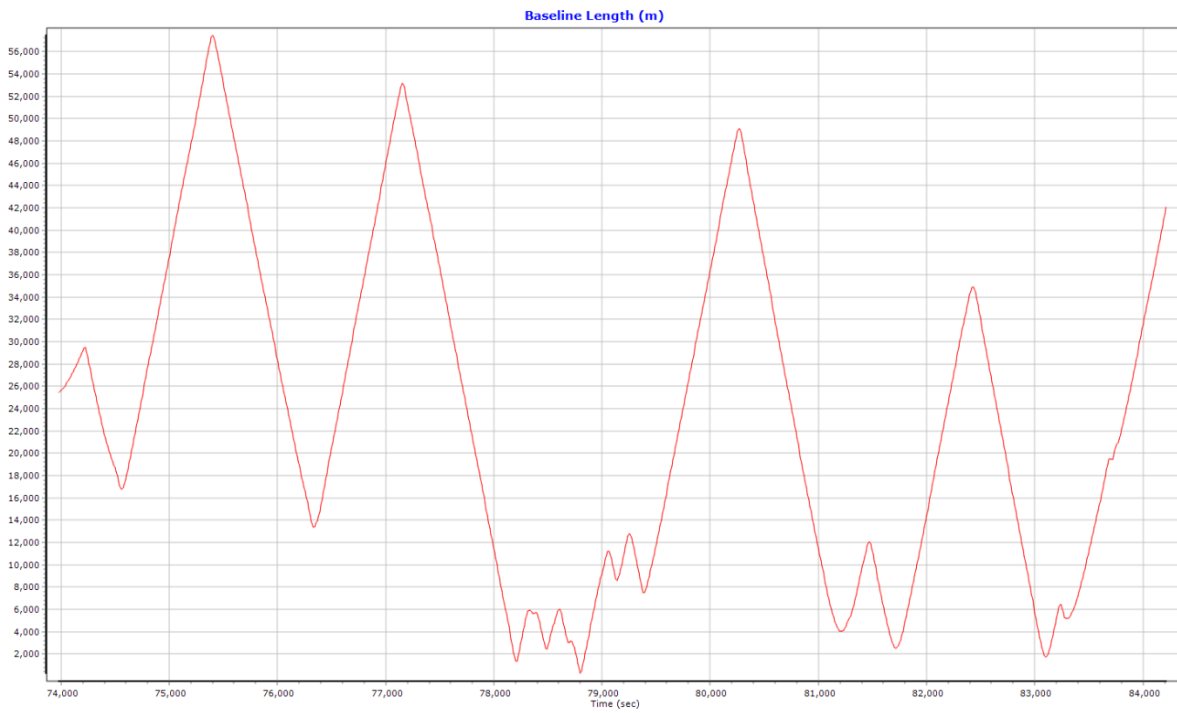
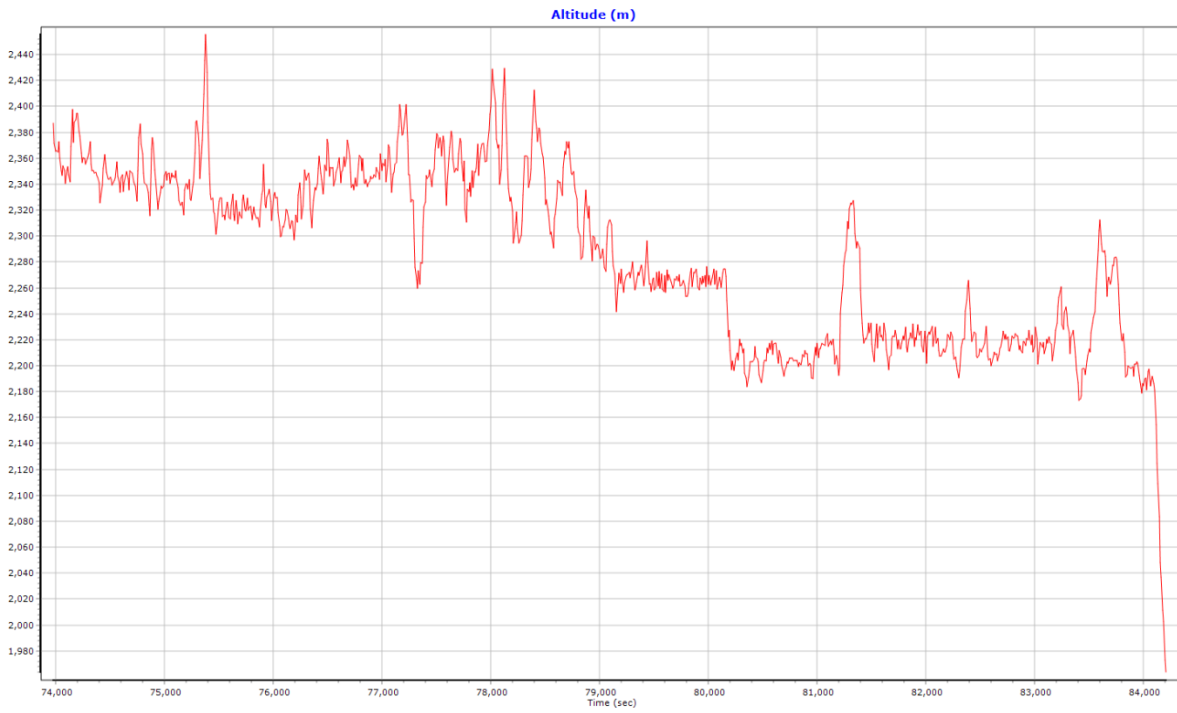


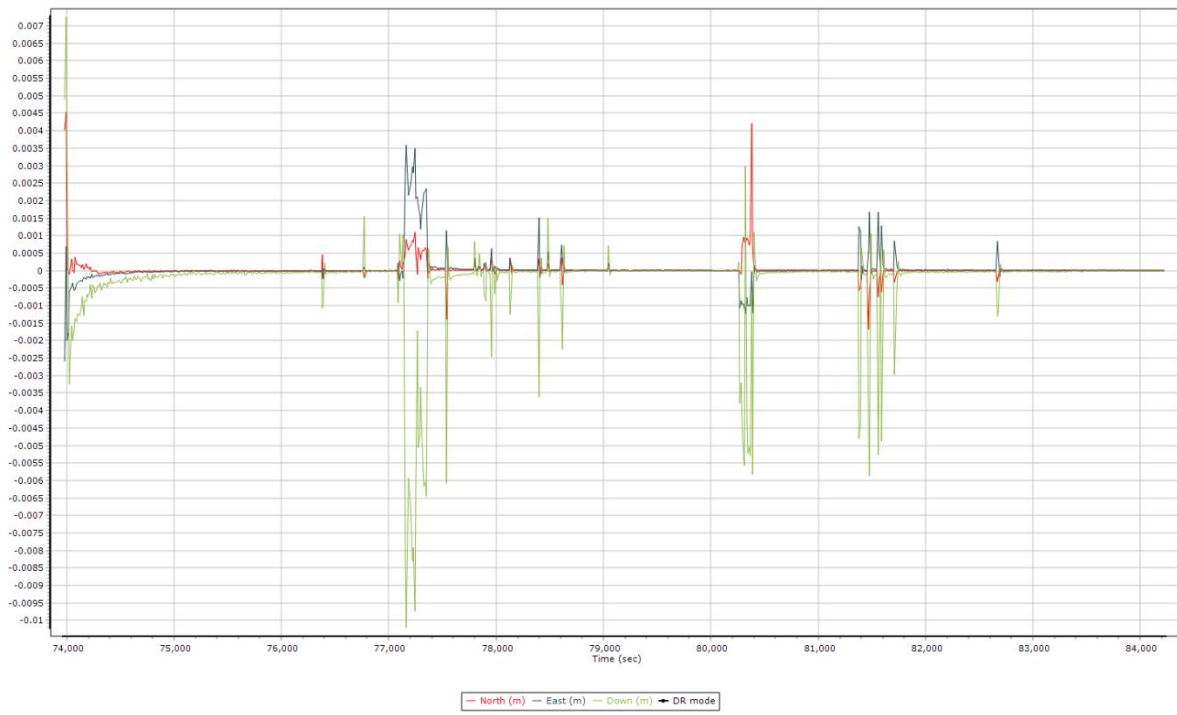
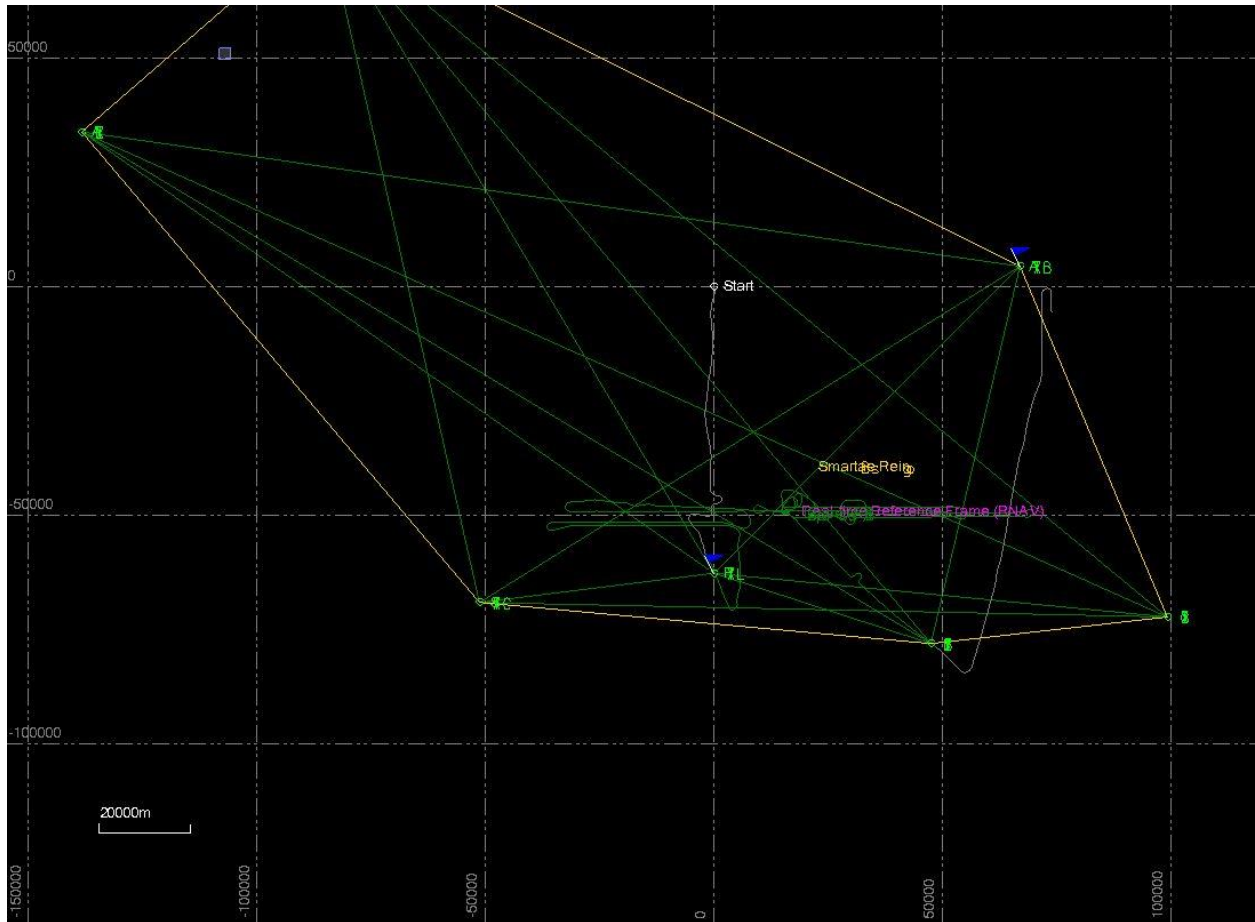


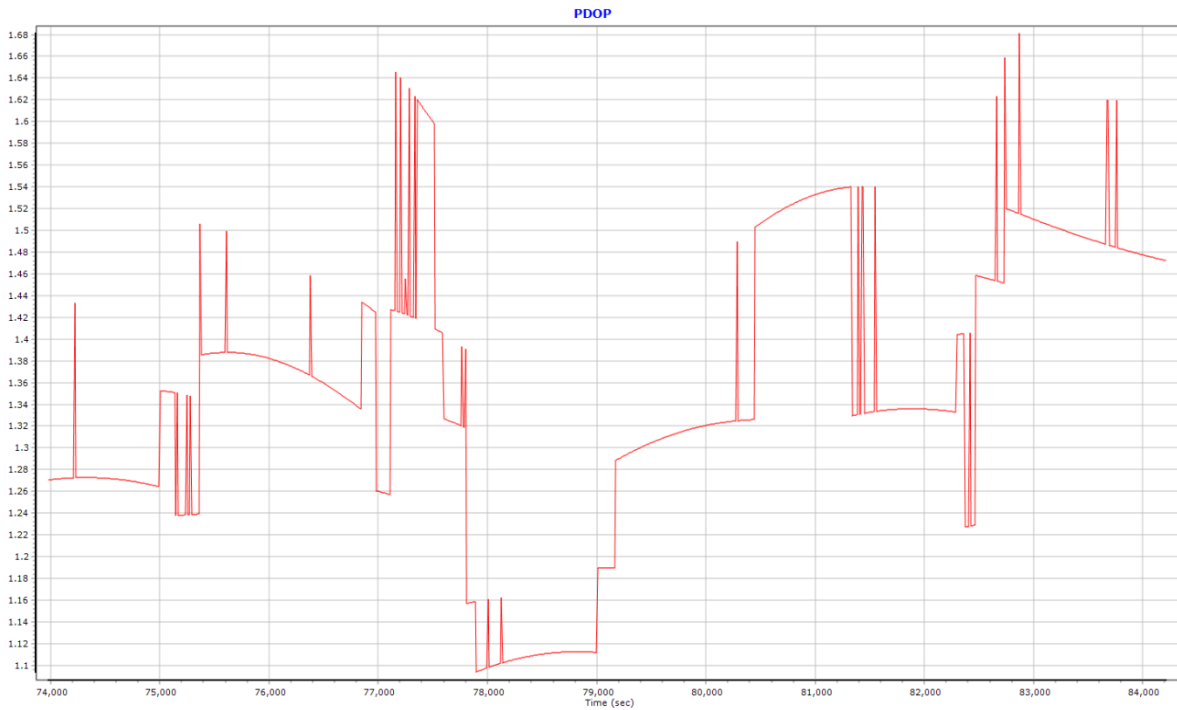
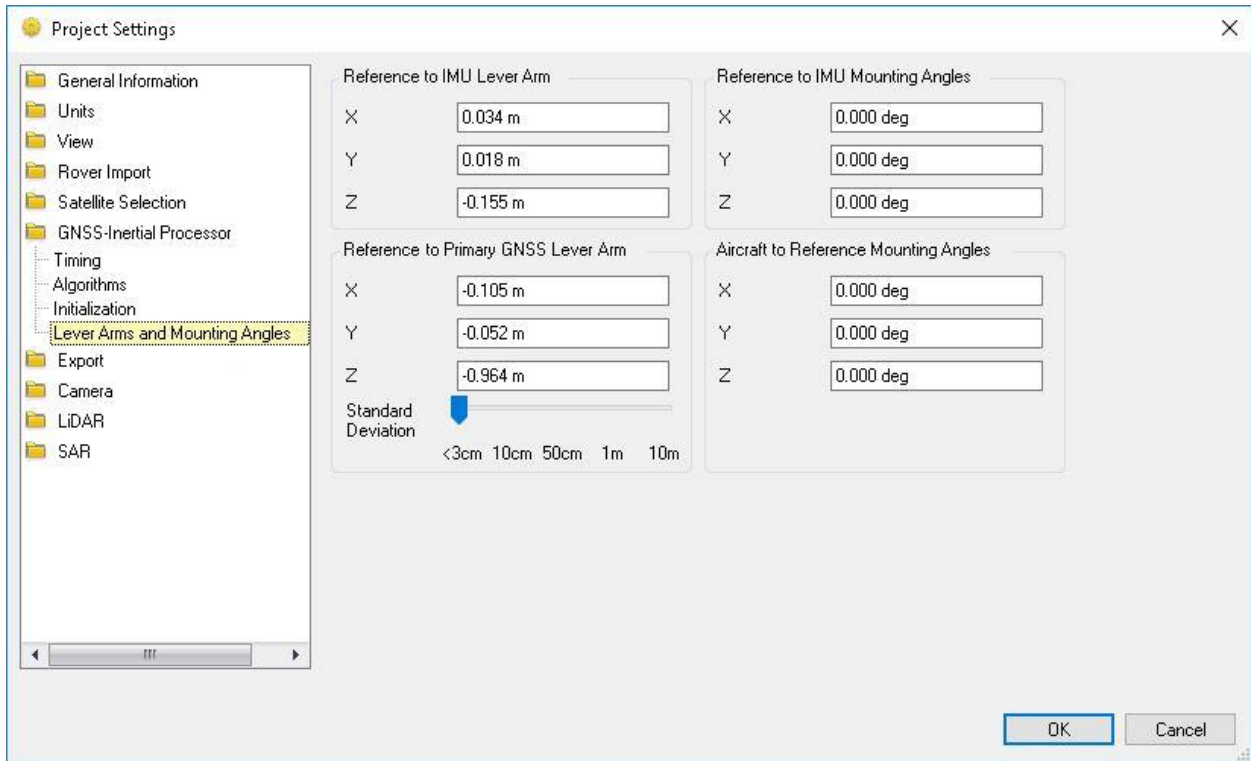


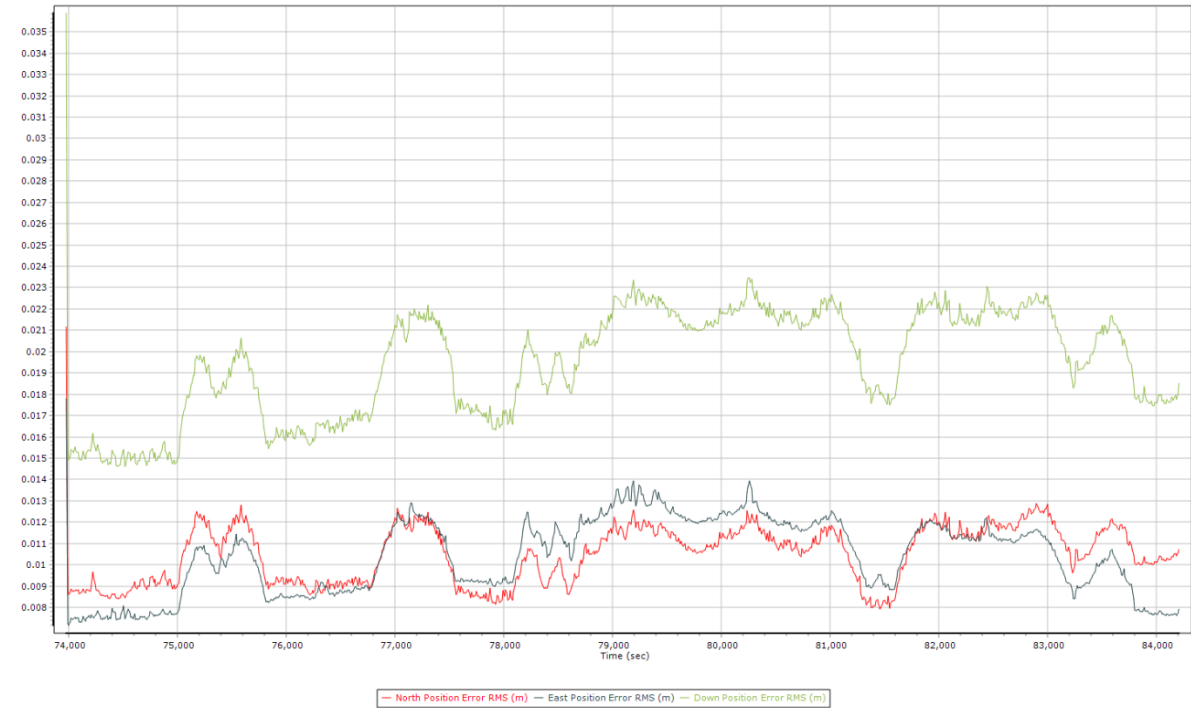


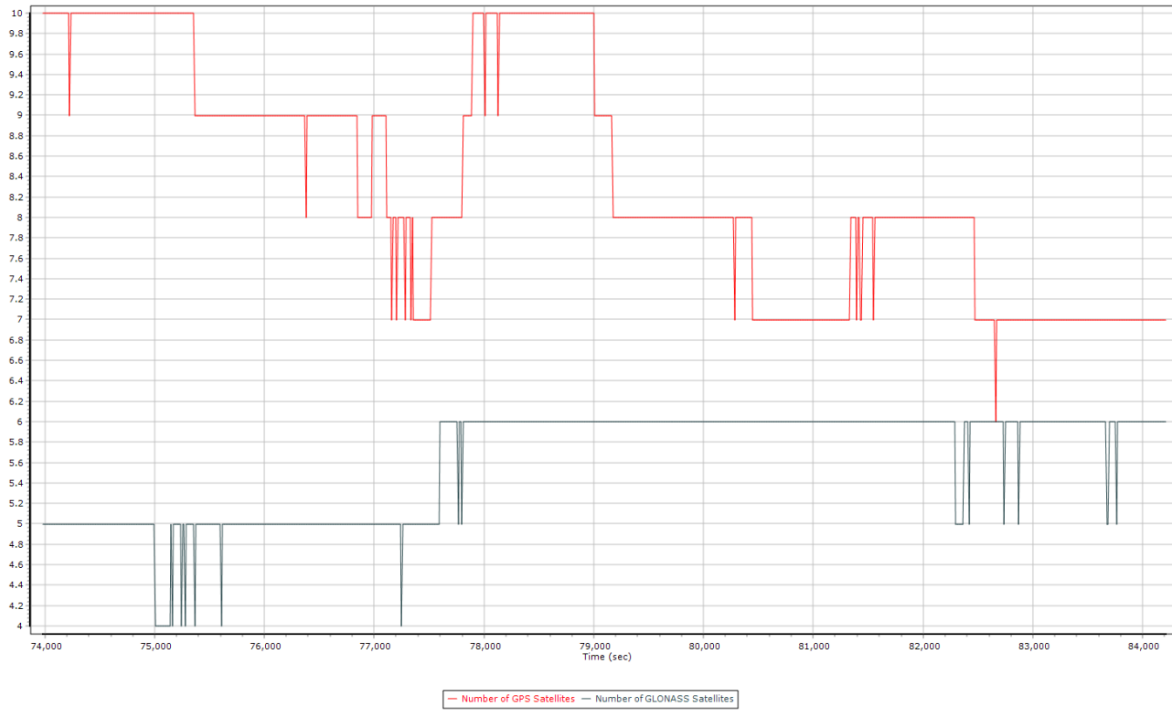
UNB18126B











Project Settings [X]

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

Timing

Start: 73978.370
 End: 84229.767
 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

