

WinFrog Device Group:	GPS
Device Name/Model:	NAVSTAR XR5M
Device Manufacturer:	<p>Symmetricom Navstar Systems Ltd. Mansard Close, Westgate Northampton, UK, NN5 5DL Tel: +44 1604 585588 Fax: +44 1604 585599 E-mail: navstar@symmetricom.com</p> <p>Available via: TDC Interactive Stroudley Road, Basingstoke, Hampshire, RG24 8FN United Kingdom</p>
Device Data String(s) Output to WinFrog:	Pseudorange and Ephemeris Data
WinFrog Data String(s) Output to Device:	Nil
WinFrog .raw Data Record Type(s):	PSEUDORANGE 303

DEVICE DESCRIPTION:

The NAVSTAR XR5 is manufactured by Symmetricom Navstar Systems Limited, which is a supplier of the United States Department of Defense. These systems are designed to meet US Military specifications. The XR5 is equipped with three communication ports and a 486-computer processor. The newer version of this instrument is the Sharpe XR6.

DEVICE CONFIGURATION INSTRUCTIONS

WINFROG I/O DEVICES > EDIT I/O:

Baud Rate: Configurable 300-19,200 software selectable
Data Bits: Configurable
Stop Bits: Configurable
Parity: Configurable

The unit can accept RTCM SC-104 differential corrections and output a differentially corrected solution.

WINFROG I/O DEVICES > CONFIGURE DEVICE:

The Navstar XR5-M is added to WinFrog from the GPS device category. Adding the Navstar XR5-M device provides Pseudorange and Ephemeris data items. There is no configuration required or available in the I/O Device window.

WINFROG VEHICLE > CONFIGURE VEHICLE DEVICES > DEVICE DATA ITEM > EDIT:

As mentioned above, there are two data items available with the XR5-M device: Pseudorange and Ephemeris. The Ephemeris device requires no configuration to suit the vehicle application.

The PSEUDORANGE data item must be edited once it is added to a vehicle's device list. Highlight the data item in the vehicle's device list and click the Edit button. The Pseudorange Calculation dialog box appears as seen below.

The screenshot shows the 'Pseudorange Calculation' dialog box with the following settings:

- Calculation:** Primary, Secondary
- Accuracy:** 1.0 Position, 0.10 Velocity
- Remote Unit ID:** 0
- Multiple Position Source Options:** Disable Auto Switching of Primary, Enable Auto Switching of Primary, Age of primary data when switch is to occur: 10sec
- Antenna Height:** Ellipsoid Height: 30.00m, Calcd, Auto\Last Hgt, Fixed, Auto\Input Hgt
- Offsets:** Fore/Aft: 0.00m, Port/Stbd: 0.00m, Height: 0.00m
- DGPS Mode:** Auto, On, Off, Generate
- Phase Smoothing:** Apply Phase Smoothing, Filter Length: 25, Cycle Slip Tol: 8
- Graphics:** Off, On
- Display:** Results, Data, Statistics
- Use For Heading Calculations, Use Elevation
- Buttons: Alarms, Tests, RefStns, OK, Cancel, Help

Calculation:

Set the Calculation selection to Primary or Secondary. Devices set to Primary calculation are used to provide a vessel position. Note that more than one Primary positioning device can be added to a vehicle's device list; data from these devices

will be combined in a weighted mean solution. (See the paragraph on Accuracy below for more on the weighting of Primary calculation device data).

If the Calculation type is set to Secondary, WinFrog will simply monitor the device's data. WinFrog will not use the data from a secondary device in the final solution of the vehicle's position.

If auto switching is enabled (see below) a secondary may automatically become a primary should all the primaries fail.

Accuracy:

The Accuracy value entered provides WinFrog with the expected accuracy of the position from this device. This value is used in the weighting of this device compared to other positioning devices that may be added to the vehicle's device list. The smaller the value entered, the more accurate it is considered to be, and hence the more weight that will be applied to the device's data. The Accuracy parameter can be changed from the suggested values, although changes should be made with caution, as they will affect the final filtered position of the vehicle.

The Velocity value is used in positional filtering. The lower the value entered, the more smoothing that is applied.

Remote Unit ID:

The Remote Station ID parameter is set to zero (0) unless the GPS device is interfaced to WinFrog via a telemetry device.

Multiple Position Source Options:

This group box allows you to enable automatic switching of a secondary to primary should the data from all POSITION and PSEUDORANGE data items set to primary timeout. The **Age** entered is the length of time that the secondary will wait in the absence of data from all primaries, before taking over as primary. This age is only entered for the secondary.

For example, if the POSITION or PSEUDORANGE data items associated with two GPS receivers were set to primary and the POSITION or PSEUDORANGE data item of a third GPS receiver was set to secondary, both primary GPS receivers must time out before the secondary will become the primary. Upon the recovery of either of the original primary data items, the original primary will be reset to primary and the original secondary will be reset to secondary.

Note for the auto switching feature to work, there must be at least one primary and one secondary enabled. For example, given two data items, one set to primary with the auto switching disabled and the other set to secondary with the auto switching enabled, if the primary fails the secondary is not set to primary and the vehicle positioning stops until the primary data item recovers.

Disable Auto Switching of Primary:

If this data item is not to be involved in the auto switching process, check this box. As stated above, this data item is then not involved in the auto switching process in any way.

Enable Auto Switching of Primary:

If this data item is to be involved in the auto switching process, either as a primary or a secondary, check this box. If set to secondary, enter the Age of data the primary data items must reach before this secondary is switched to act as the primary.

In order for this option to be effective you must have at least one primary and one secondary. If there are multiple secondary data items that are enabled for switching, the first one to receive data will become primary.

Note: This option is not enabled unless WinFrog determines that there is more than one POSITION and/or PSEUDORANGE data item associated with the respective vehicle. The exception to this is the case of a WinFrog with the Remote module operating as a Controlled Remote being configured remotely from the Controller. In this case, the option is always enabled even though it may not be applicable. The operator must be aware of what is available on the Remote and configure the data item accordingly.

Note: This option is not available in the WinFrog Remote package.

Antenna Height:

Set the Antenna Height using the radio buttons and the (input) Ellipsoid Height field. Settings are as follows:

Calculated – Select this option to force WinFrog to calculate the GPS antenna Height, as well as its Latitude and Longitude. In this mode, WinFrog requires a minimum of four satellites to be visible.

Fixed – Select this option to fix the GPS antenna ellipsoid height to the value entered in the **Ellipsoid Height** field. In this mode, WinFrog is able to calculate valid positions using a minimum of three satellites.

Auto\Last Height – If this mode is selected, WinFrog will calculate a 3D position if four or more satellites are available. If only three satellites are visible, or if the VDOP of the solution exceeds the value set in the Alarms dialog box, the height is fixed to that of the last valid position. In this mode WinFrog is able to calculate valid positions using a minimum of three satellites.

Auto\Input Height – If this mode is selected, WinFrog will calculate a valid 3D position if four or more satellites are available. If only three satellites are available, or if the VDOP of the solution exceeds the value set in the Alarms

dialog box, the height is fixed to the value entered in the **Ellipsoid Height** field. In this mode, WinFrog is able to calculate valid positions using a minimum of three satellites.

Note: The Antenna height entered in the **Pseudorange Calculation** dialog box refers to the WGS 84 Ellipsoid.

Offsets:

Offsets are entered to relate the GPS antenna position to the vessel's Common Reference Point (CRP). Offsets are entered as measured from the CRP (of the vehicle) to the device (antenna) location. Offsets Fore and Starboard are entered as positive values, offsets measured Port and Aft are entered as negative values. Rule of thumb suggests the CRP "Z" reference should be at the water line.

DGPS Mode:

Select the desired mode of DGPS operation

There are four different DGPS modes: Auto, On, Off and Generate.

Auto: WinFrog will automatically use differential corrections in its position calculations, when available. If no corrections are available, WinFrog will compute a single point (autonomous) position solution.

On: WinFrog will always attempt to use differential corrections. If no corrections are available, no position will be computed.

Off: WinFrog will not use differential corrections in its position computations, even if they are available. Instead it will always compute a single point GPS solution.

Generate: WinFrog will generate differential corrections based on a fixed reference position. This option is used for Base Stations only.

Phase Smoothing:

Phase smoothing utilizes the GPS receiver's observations of the GPS satellite's carrier signals. Because the GPS L1 frequency has a wavelength of only 19 cm., measurements made using this signal will provide higher accuracy than measurements made on the C/A code message modulated onto the L1 signal. Note, however, that since the carrier phase position is derived from the C/A code position, it does not offer an improvement in precision.

If the Phase Smoothing feature is enabled, WinFrog will use the C/A Code derived (DGPS corrected) position to derive the number of L1 wavelengths to each of the observed satellites. Over the length of time entered into the **Filter Length** field (value in seconds), WinFrog will switch the GPS calculated position from the C/A code position to the derived Carrier Phase position.

WinFrog will continue to use the carrier phase data to provide positioning until the **Cycle Slip Tolerance** is exceeded. A Cycle Slip is the loss of lock on a satellite's signal. This loss of lock forces WinFrog to re-establish the number of wavelengths from the antenna to the satellite. If the number of cycle slips exceeds the Cycle Slip Tolerance, WinFrog will resort back to the C/A code position and re-calculate the number of wavelengths to all received satellites.

Graphics:

Select the On radio button to display a labeled square in the Graphics and Bird's Eye displays depicting the raw (unfiltered) location of the GPS antenna. This provides a means of comparing raw and filtered positions between different sources.

Display:

The selection made here determines which type of information will be displayed in WinFrog's Calculations window (when the GPS Pseudorange device is turned on for display in that window). Select from the three provided options:

Results – The Calculations window will show the results of the GPS Calculations, including the Multi-Ref position and all individual solutions.

Data - The Calculations window will show the results of the GPS Calculations, including the Multi-Ref position and data related to each individual carrier phase solution (when Phase Smoothing is enabled).

Statistics - The Calculations window will show the results of the GPS Calculations, including the Multi-Ref position and statistical data related to each individual solution.

Use For Heading Calculations:

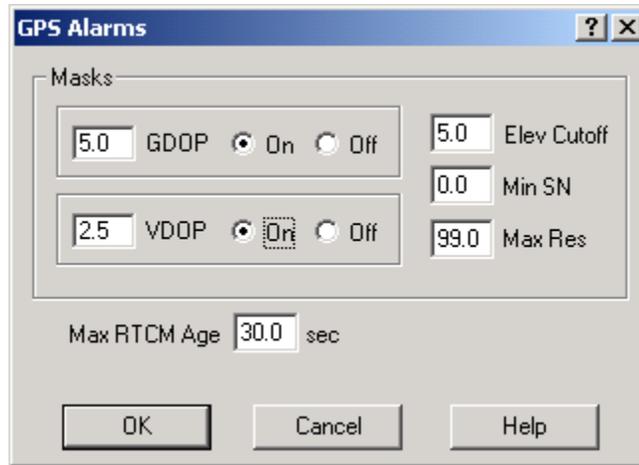
Select this checkbox if the device is to be used in conjunction with another GPS device for determination of heading of the vessel. In most cases, only high accuracy receivers should be used for heading calculations as WinFrog simply inverts the individual sensors' raw positions to derive the bearing between them.

Use Elevation:

Setting the Elevation option to "On" will result in the elevation determined by GPS to be used as the elevation of the vessel's CRP referencing the GPS (WGS84) Ellipsoid. The height of the antenna above (below) the CRP must be entered. Do not enable this option unless you are utilizing high accuracy (centimeter level) RTK type GPS positioning.

Alarms:

Click this button to view and enable various GPS alarms, as described below.



GDOP – Geometric Dilution of Precision. GDOP is a numerical value that serves as a measure of the effect of the satellite constellation’s geometry on the derived positional accuracy. In other words, the GPS receiver’s measurement accuracy is multiplied by the GDOP value to derive the overall positional accuracy of the GPS receiver (including the three positional dimensions and clock offset). If the GDOP mask is set to On and the calculated GDOP exceeds the entered value, WinFrog will not compute a position solution using pseudoranges. If the Calculations window is enabled, an alarm will sound to indicate that the GDOP has been exceeded.

VDOP – Vertical Dilution of Precision. This parameter is also calculated from satellite geometry and gives an indication of the expected accuracy of the vertical component of the GPS position solution. If the VDOP mask is set to On and the calculated VDOP exceeds the entered value, WinFrog will automatically initiate 2D or fixed height mode using either the last valid calculated height or the height entered in the Antenna Height **Ellipsoid Height** field. If the Calculations window is enabled, an alarm will sound to indicate that the VDOP has been exceeded.

Elev. Cutoff – (Elevation Angle Cutoff). WinFrog will not use measurements from any satellites with elevation angles below the angular value input in the Elevation Angle Cutoff field. Any satellites not used in the pseudorange position calculations are indicated in the Calculations window by a change of color.

Min SN – Minimum Signal to Noise. This field is used to set the minimum signal to noise ratio for the pseudorange calculations. If a satellite’s signal to noise ratio falls below the entered value, the satellite will not be used in position computation by WinFrog. Satellites not used in the position computation due to low signal to noise values are indicated in the Calculations window by a change of color.

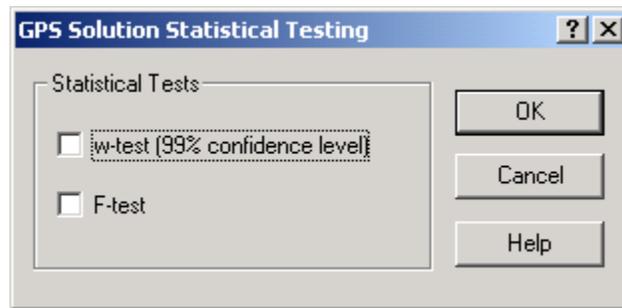
Max Res – Maximum Measurement Residual. WinFrog will not use any satellite measurement with a residual greater than the Maximum Measurement Residual in its pseudorange position computations. Satellites not used in the position

computation due to measurement residuals are indicated in the Calculations window by a change of color.

Max RTCM Age – Maximum RTCM Differential Correction Age. This parameter sets the maximum latency of real time differential corrections for pseudoranges. If the maximum latency is exceeded, WinFrog will not apply the corrections from that RTCM source. To indicate this condition, the **STAT** light in the Position portion of the Calculations window will turn yellow. Click on the **ACK** button to acknowledge this alarm.

Tests:

Click this button to open the **GPS Solution Statistical Testing** dialog box, as seen below.



This dialog box provides you with the ability to enable or disable statistical w test and F tests. By default, both of the w-test and the F-test are turned off.

w-Test:

The w-test entails normalizing the residuals of a GPS pseudorange solution and testing these against a 99% confidence limit for outliers. This limit is 2.576. If outliers are found, they are removed and the solution is re-executed excluding that satellite data pertaining to the outlier. If more than one satellite is found to produce a residual outlier, only that satellite with the largest normalized residual is eliminated. This continues until no outliers are present *or* until the exclusion of any more data would result in insufficient data for a solution (four satellites for 3D and three for 2D). Since the normalized residuals tend towards being equal with reduced redundancy (as the number of satellites used in the solution approaches the minimum required), it is unlikely that WinFrog will ever have to stop the exclusion of data due to insufficient satellites. Nonetheless, WinFrog still checks for this condition.

Caution should be exercised when using this option. If the vessel is too far away from the selected reference stations and/or there are few satellites in common with the vessel and the reference station(s) the w-test option may eliminate data to the point where the solution approaches the minimum required.

F-Test:

The F-test is a check of the unit variance of the GPS pseudorange solution. This confirms the validity of the model used for the solution and the weighting of the observations used. Note that it is only a confirmation check, no data or solution results are thrown out based on the results of the test.

The unit variance is the sum of the weighted, squared residuals, divided by the degrees of freedom (number of redundant measurements) in the solution. The F-Test should result in unity. If the unit variance is consistently different from unity, it indicates that there may be a problem with the stochastic model used, or an unmodeled bias in the data.

RefStns:

Click the RefStns button in the Pseudorange Calculation dialog box to open the Select DGPS Reference Stations dialog box, as seen below.



The Select DGPS Reference Stations dialog box allows you to define which reference stations will be used by WinFrog in its Multi-Ref solution. You can either configure WinFrog to simply use all received stations (to a maximum of 5), or you can control the use of corrections, as deemed proper.

To use all received DGPS corrections, select the **Use all Available Stations** checkbox. When this checkbox is selected, all available RTCM corrections are utilized in the solution, each with the same Relative Standard Deviation.

The individual station method is preferable as it allows you to remove or de-weight solutions that may not agree with the weighted mean solution. If this method is used, you should add the RTCM data item to the vehicle's device list once for each solution, then edit that solution entering the proper code and coordinates. For example, if there are five Reference stations to be used in the Multi-Ref solution, add the **RTCM,RTCM1,DGPS-COR's** data item to the vehicle's device list five times.

From the Configure Vehicle-Devices dialog box, highlight and edit each RTCM data item to indicate a unique Code.

Now, back in the **Select DGPS Reference Station** dialog box, ensure that the Use all Available Stations checkbox is not selected. Now the individual reference station ID's must be entered, along with station usage and relative standard deviation values, as detailed below:

Select DGPS Reference Stations:

Selection of individual stations is as follows:

ID – The Reference Station identification code. See SkyFix documentation for a listing of all SkyFix reference station ID Codes. Coast Guard Beacon corrections also contain unique codes for each station.

In the above example, SkyFix stations 535, 545 and 570 are used with assigned relative standard deviations along with Coast Guard station 336. Coast Guard Station 334 is monitored and is therefore not utilized in the position solution.

Off – Corrections from the selected Reference Station will not be used in the Multi-Ref position solution. This individual solution will appear in red text in WinFrog's Calculations window and not update.

Use – Reference Station is used in the Multi-Ref position solution, and will appear in the Calculations window in black text. This individual solution will appear in red text if no solution (refer to DGPS Mode) can be calculated from the data.

Monitor – Reference Station is simply monitored by WinFrog, and is not used in the Multi-Ref position. This solution will appear in yellow text in WinFrog's Calculations window.

Rel. Std. Dev – This value defines the relative standard deviation of this solution as compared to the other solutions used in the Multi-Ref position. Equal Rel. Std. Dev. values indicate that all individual solutions will be equally weighted in the Multi-Ref solution. Entering a higher Rel. Std. Dev value will de-weight an individual solution compared to the others in the Multi-Ref solution.

CONFIGURE CALCULATIONS WINDOW

A Calculations window can be configured in WinFrog, allowing you to monitor the status of the Mult-Ref solution and make appropriate adjustments. To open the Calculations window select **View > Calculations** from the main menu. In the Calculations window, select the appropriate vehicle from the dropdown list and click the Setup button.

In the Setup Calculation Views dialog box, select the **Position** and **Data Item Text** checkboxes. Next, highlight the **Pseudorange data item**, click the **On** button and exit with OK. Refer to Chapter 14, GPS Calculations Displays section of the WinFrog User's Guide for more detailed descriptions of the various options and displays available with the Calculations window.

CONFIGURATION DETAILS:

RTCM RS-232D, RTCM SC-104, Type 1,2,3,9,20,21,12 way miniature 723/IP67
Antenna TNC connector to volute or patch antenna
Recorder RS422A, 1pps, Automatic output of data, NMEA 0183, status message,
12 way miniature 723/lp67

CDU Interface Signal:

The receiver CDU interface is via a Binder connector. The interface conforms to the EIA standard RS-232D.

<u>PIN</u>	<u>SIGNAL</u>	<u>Description</u>
1	-	Reserved
2	RTS	Request to Send
3	-	Reserved
4	CTS	Clear to Send
5	-	Reserved
6	TXD	Transmit Data
7	-	Reserved
8	RXD	Receive Data
9	-	Reserved
10	RESET	External Reset
11	GND	Signal Ground
12	ETH	Chassis Ground

The CDU interface operates a 9600-8-odd-1.

Recorder Port Signal:

The receiver data signal interface is via a Binder connector. The interface conforms to the EIA standard RS-422A

<u>PIN</u>	<u>SIGNAL</u>	<u>Description</u>
1	-	Not Used
2	-	Not Used
3	-	Not Used
4	-	Not Used
5	-	Not Used
6	TXD(H)	Transmit Data
7	TXD(H)	Transmit Data
8	-	Not Used
9	-	Not Used
10	1-PPS	Timing Pulse
11	GND	Signal Ground
12	ETH	Chassis Ground

RTCM Port Signal:

The receiver data signal interface is via a Binder connector. The interface conforms to the EIA standard RS-232D.

<u>PIN</u>	<u>SIGNAL</u>	<u>Description</u>
1	-	Not Used
2	RC	Radio Modem TX
3	-	Not Used
4	-	Not Used
5	-	Not Used
6	TXD	Transmit Data
7	-	Not Used
8	RXD	Receive Data
9	1-PPS	Timing Pulse
10	RESET	External Reset
11	GND	Signal Ground
12	ETH	Chassis Ground

RAW DATA LOGGING:

External data logging can be accomplished by interfacing a PC to the unit.

SPECIFICATIONS: (Manufactures)

Receiver: 12 channel C/A code, L1 frequency

Update rate: Status message output up to 4 times a second

Power 11-32VDC, 3-way miniature 723/IP67

Beacon Differential 1-3m CEP (RTCM 20+2/9), velocity 0.03m/s

Performance Characteristics:

Receiver: 12 Channel C/A code, L1 frequency.

Satellites: Up to 12 satellites tracked.

Update rate: Status message output up to 4 times a second.

Velocity: Maximum speed, Mach 2, Maximum acceleration 6 g jerk 4 g/s, 1 pps +/-50 nanoseconds.

Time to first fix: <30 seconds (with current ephemeris).

Enclosure: Pressure die cast aluminum box, size: 175 mm x 80 mm x 57 mm, weight: 1 kg.

Finish: Stove Enamel.

Interfaces: RTCM SC-104, CDU (Control & Display Unit): RS232D, NavStar DM, 1 pps, NMEA 0183, status message.

Baud rate: 300-19,200 software selectable +/-0.1%.

Power: 9-32 Vdc 3-way miniature 723/IP67.

Antenna: TNC connector to volute or patch antenna.

Power: 5 watts average at 12 volts.

Protection: Protected against reverse connection, excessive voltage, transients and over temperature.

Temperature: Operating -20° to +65°C.