Survey Grade INS

External NMEA GNSS integration

Operating handbook

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SBG SYSTEMS

This brief document guides you in the process of connecting an external NMEA GNSS receiver to your SBG INS (All-in-One or Navsight).

Step 1: GNSS and Sensor connections

Connect GPS Tx signal(s) to one of the following pins on device connectors: PORT A, B, C, D, E Rx pins.

You can also use an Ethernet connection if required – not covered by this document.

Connect GPS PPS signal to Sync A, B, C, D or E input.

Note 1: Only the physical PORT A is available for the All-in-one Ekinox / Apogee-A. You can still use Eth 1 to Eth 4 virtual serial ports to input GPS data.

Step 2: GNSS module configuration

Configure the following outputs and output rates on your GPS receiver:

- **RMC** @ 5 Hz
- **GGA** @ 5 Hz
- **GST** @ 5Hz
- **HDT** @ 5 Hz (if applicable, on dual antenna systems)
- **ZDA** @ 1Hz

In addition, the GPS **PPS** signal must be sent at 1 Hz for proper operation.

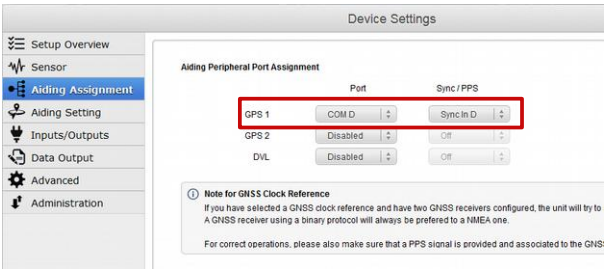
Step 3: Sensor configuration

In order to configure the Sensor, you need to connect to the Web interface and open the configuration window. Simply follow those instructions:

Set Aiding Assignment

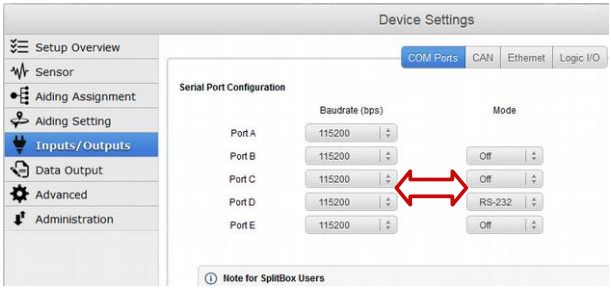
In this window, you just indicate where you connected your GNSS receiver.

Both communication port **and** Sync In pin must be set.



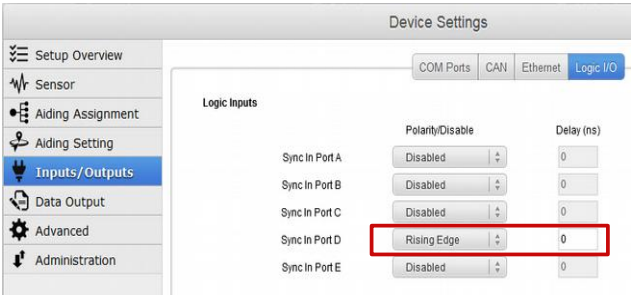
Set correct baudrate and mode for serial port

In our example we configured the GPS to be connected on PORT D in RS-232 mode.



Set Logic input configuration for PPS signal

In order to use correctly PPS signal information, you must enable the corresponding logic input.
Here we configured PPS on Sync D.
Polarity should be set accordingly with the actual GPS signal.



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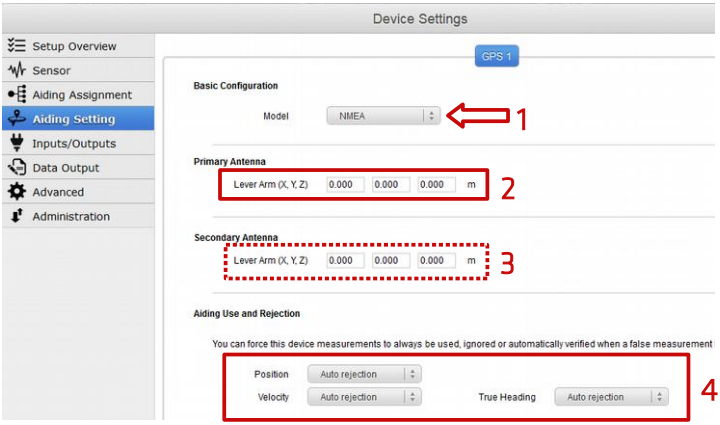
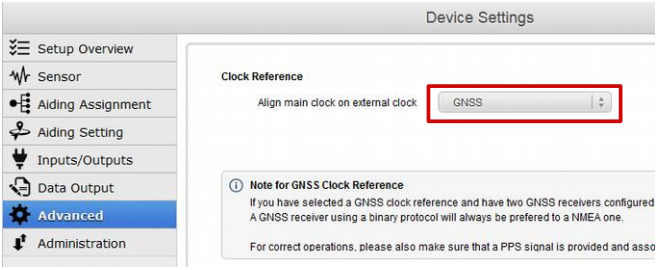
Set correct GPS model and configuration

1. GPS model should be set to NMEA (select the NMEA Trimble/Ashtech is it is one of these receivers as the heading is referenced the other way around with those GNSS receivers)
2. GPS lever arm is measured within 5cm **FROM** the IMU, **TO** the antenna.
3. In case of Dual antenna system, offset for the secondary one (providing heading) must also be entered, from the IMU, To the antenna.
4. Finally, each available measurement (position, velocity and true heading if available) should be configured to be used or not.



Set Clock alignment

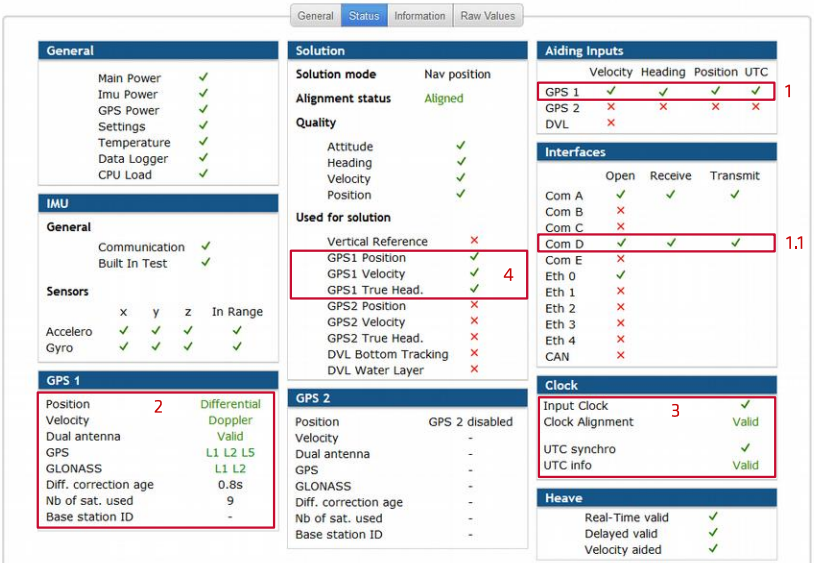
Finally, you should define which GPS should be used to align the internal clock and provide UTC time data. This is done into the advanced settings section:



Note: If you have two connected GPS receivers, the Sensor doesn't need a PPS signal for the second GPS receiver to accurately time stamp the data.

Step 4: Checking status

Once fully configured, the global status must be checked:



1. GPS 1 or 2 line in "Aiding Inputs" section must show valid data. Check next items otherwise:
   - Check interface configuration (1.1): Corresponding COM port must be opened and Rx flag OK. Baudrate should be the same in the GPS and the SBG unit configuration
   - Check for hardware wiring issues
2. GPS solution is reported in that section. Check if there is a good GPS fix here.
3. Then you can check at the Clock section. Input clock must be OK and UTC time should be set to valid after a few minutes in alignment mode.
4. Once the GPS acquired a solution, the Kalman filter should pass in Full Navigation mode and show active items in the "Used for Solution" field.

Note: The Kalman filter will run into navigation mode once a correct heading could be estimated (requires magnetometers, true heading or some accelerations).

Note 2: Position data should be used in solution in good GNSS environments. In case of RTK fix, the velocity aiding is automatically disabled for optimal performance.