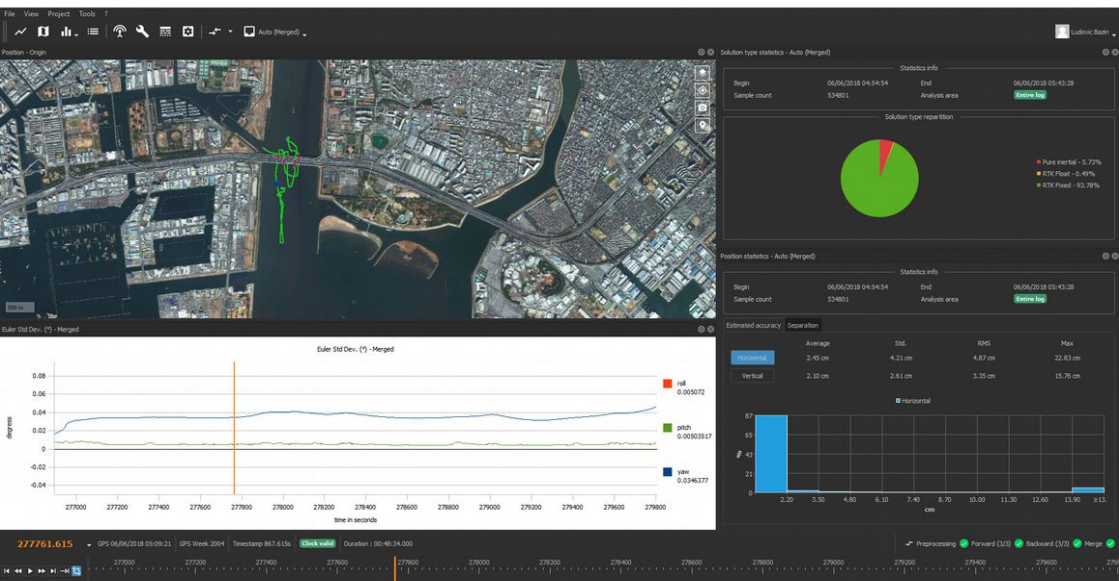


# — Ekinox and Apogee Series

## Post Processing guide

### Operating handbook



Document  
Revision

AEKOHPP  
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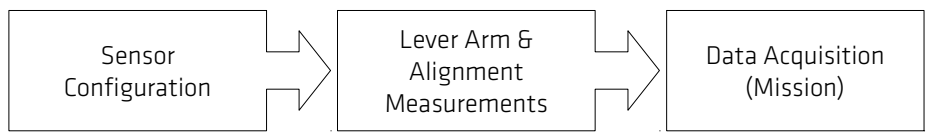
*This brief document explains how to setup the Ekinox or Apogee INS for post processing with Qintertia and details the workflow from data acquisition to post processed results.*

## Post Processing Workflow

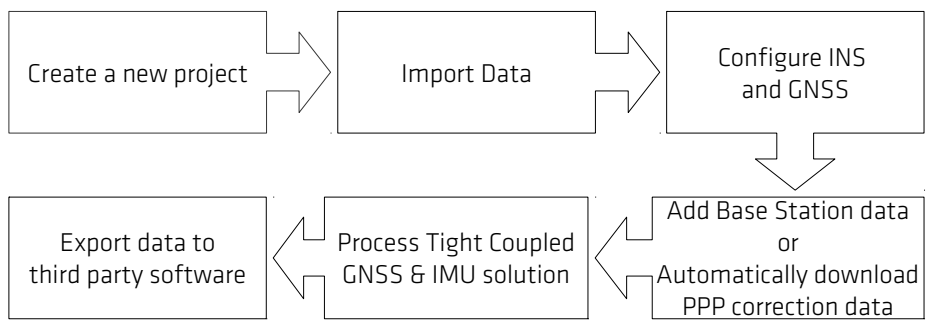
The processing workflow can be divided into two parts. The first one consists of configuring the sensor correctly and acquiring data thanks to the internal data-logger.

The second one is the post-mission part that is basically, getting the data from the INS, creating a project in Qintertia, computing a post processed GNSS + IMU tight coupled solution and exporting data to the desired format.

### Data acquisition



### Post-Mission workflow



# Before you start

Post processing is officially supported on Ekinox and Apogee INS when used with the internal GNSS receiver. To be used for post processing operations, the GNSS receiver connected to the INS should be able to output RAW data.

You can easily check if your internal receiver supports post processing by accessing the information panel on the embedded web interface. The Master GNSS should include the RAW option as you can see on the screenshot below:

General

Status

Calibration

Information

Raw Values

Firmware Details

Firmware version

Current version: 2.0.297-stable

Upload firmware

✓ Firmware up to date

GNSS options

Upload license

Detected Master GPS

Show Details

Information for Master GPS

Identification

Product Code

CDSW0G550

Serial Number

BMES16251293F

Hardware Version

OEM617D-1.00

Firmware Version

OEM060600SN0056

Signals

GPS

L1/L2

GLONASS

L1/L2

BEIDOU

B1/B2

Galileo

Not Permitted

QZSS

Not Permitted

SBAS

Permitted

L-Band

Not Permitted

Features

Dual Antenna

Permitted

RTK

Permitted

PPP

Not Permitted

RAW

Permitted

RAIM

Not Permitted

NATO

Not Permitted

Output Rate

5 Hz

L-Band decoder

Activation Code

N/A

User ID

N/A



**Note:** If your GNSS doesn't support RAW GNSS data logging, please contact your sales representative to discuss available options.

# Step 1: Sensor configuration

## Set Aiding Assignment

Binary protocol from Novatel, Septentrio or Trimble are mandatory to be able to log raw GNSS observables. All products with an internal GNSS receiver are able to provide RAW data for post processing.

In this window, please make sure that the GNSS receiver is set properly as GPS 1 module (right protocol or internal selected):

☰ Setup Overview

📶 Sensor

⚙️ Aiding Assignment

**🧭 Aiding Setting**

🔌 Inputs/Outputs

📄 Data Output

⚙️ Advanced

🔒 Administration

GPS 1

**GNSS Setup**

Select the receiver model and if you plan to use single or dual antenna mode.  
Dual antenna heading is useful for low dynamics applications and to initialize the INS in static conditions.

Receiver ModelInternalGNSS Heading ModeDual antenna (known lever arm)

**GNSS Lever Arms**

Please enter the primary and secondary lever arms FROM the INS, TO the GNSS antenna with an accuracy better than 1 cm.  
If you plan to use the calibration mode, please at least provide lever arms with an accuracy better than 20 cms

Primary Antenna (X,Y,Z)-0.372-0.817-0.163 mSecondary Antenna (X,Y,Z)-0.3720.613-0.169 m

**Aiding Use and Rejection**

You can change the rejection filter to define how the INS should use the measurements coming from this GNSS.  
To use in the INS solution both Position/Velocity and True Heading measurements from this GNSS receiver, please select Auto Rejection.  
Auto rejection is the preferred mode as the INS will detect and ignore inconsistent measurements automatically.

Position/VelocityAuto rejectionTrue HeadingAuto rejection

You can also enable the odometer if you are planning to use a DMI.

Any differential corrections sent to the Device (RTCM data) will only improves the real time solution. They will not be used in the post processed solution (corrections should be logged on the base station).

## Data-logger configuration

All messages needed to compute a post processed solution can be logged into the sensor internal data-logger.

Please select the “Post-Processing” output preset for quick output configuration.

Alternatively, and for reference, the following messages must be set to enable the post-processing capability:

- **System Status** @ 1 Hz
- **Inertial Data** @ 200 Hz
- **UTC** @ New Data
- **GPS 1 Velocity** @ New Data
- **GPS 1 Position** @ New Data
- **GPS 1 True Heading** @ New Data (\*)
- **GPS 1 Raw data** @ New Data
- **Odometer** @ New Data (\*)
- **Heave** @ New Data (\*)
- **Delayed Heave** @ New Data (\*)



**Note:** All output logs marked with an \* are not mandatory for correct post processing operations. You can freely enable or disable these logs according to your setup.



**Note 2:** If you have several GNSS receivers sending data to the INS, you should also set GPS 2 on New Data to allow Post Processing with one or with the other.

## Set Clock alignment

Finally, you should make sure that the GPS 1 is used to align the internal clock and provide UTC time data.

The post-processed solution can only be computed if data are correctly aligned and time stamped to the GPS time.

**Setup Overview**

- Sensor
- Aiding Assignment
- Aiding Setting
- Inputs/Outputs
- Data Output
- Advanced**
- Administration

**IMU Measurement Point**

Select the IMU reference point to use: Cover Target

**Altitude mode**

Select the preferred altitude to output: Enhanced

**Clock Reference**

Align main clock on external clock: GNSS

**Note for IMU Reference Point**

You can select which point to use as a reference for all mechanical installation measurements.  
The "Bare IMU" mode doesn't apply any offset on physical IMU data.  
If you select "Cover Target", the (0,0,0) point will be set to the center of the frame reference drawn on top of the IMU cover.

**Note for GNSS Clock Reference**

If you have selected a GNSS clock reference and have two GNSS receivers configured, the unit will try to select the most appropriate one.  
A GNSS receiver using a binary protocol will always be preferred to a NMEA one.

For correct operations, please also make sure that a PPS signal is provided and associated to the GNSS receiver module.



## Step 3: Lever arms, alignments & data acquisition

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### Lever arms

Configuring lever arms on the INS web page will not impact post-processed results. Indeed, this configuration is only used by the product to compute the real time solution.

You will have to re-enter the lever arms setup in Qinertia to compute a correct post processed solution.

You should thus measure them accurately and keep this information for later post-processing.

### Alignments

Unlike for lever arms, if you configure a specific alignment between the INS and the vehicle, it will affect directly the IMU data used by the post processing software. You will obviously have to enter alignment correction only once; either in the INS or Qinertia.

SBG Systems recommend that you enter the alignment corrections on the INS rather than in Qinertia so you can use the same workflow for both real time and post-processed operations.



**Note:** Even if you enter an incorrect miss-alignment in the INS configuration, you can still fix this issue in the post processing software.

### Data acquisition

As for real time operations, you will get better results if you can perform good calibration runs with vehicle dynamics at the beginning and ideally at the end of the log.

These calibration runs help the Kalman filter (either real time or post processed one) to observe and correct for mechanical installation parameters (lever arms) and sensors errors.

Please also make sure that the first and last parts of the log are in a **clear view of sky** to ensure correct and easy initial alignment procedure.

Finally, it's only possible to re-process ONE session as the logged data should be contiguous so don't split your run into multiple sessions or you will not be able to post process the data. You can't combine different sessions as you will have missing data between two different sessions.



**Caution:** Don't split logged data into multiple sessions or you will not be able to post-process the data correctly.



## Step 4: Retrieve data from the INS

The INS will log all data needed for post processing operations within its internal data-logger.

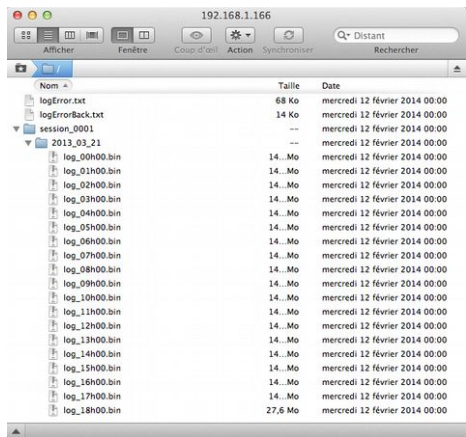
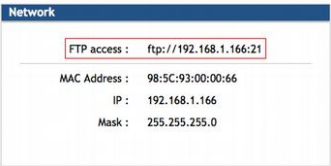
To access the files stored in the internal data-logger, please use a dedicated FTP client such as FileZilla, Transmit or Cyberduck.

To read the INS ip address, connect to the embedded webpage and browse to the information page as shown on the screenshot.

No password is required for the anonymous FTP access.

The window on the right shows the data-logger files tree structure. You will typically retrieve a whole session (session\_0001 in this case).


To find more information on the FTP and on the internal data-logger, please refers to the Technical Reference Manual.





# Step 5: Configure your Qinertia Project


Start up Qinertia, then select New Project from the Dashboard.


Create a new project

 Airplane

 Automotive

 Helicopter

 Marine

 UAV

Project name

Post Processing on UAV

Organization name

SBG Systems

User name

Anne O. Nymes

Save project to

C:\Users\Nicolas\Documents\Demo\UAV Tests - Ekinox 2

Browse

Import from directory

C:\Users\Nicolas\Documents\Demo\UAV Tests - Ekinox 2\Logs\over

Browse

SBG Systems INS detected


☒ Qinertia has detected in the selected import directory INS project.  
Please select which files you would like to import to make sure data are contiguous.

File name

UTC Begin

UTC End


Data rate

 log\_11h00.bin

05/12/2017 11:36:12


05/12/2017 11:59:21

200 Hz



**Caution:** Qinertia will merge data from multiple binary logs, but you should make sure they are continuous in time with no data gap.

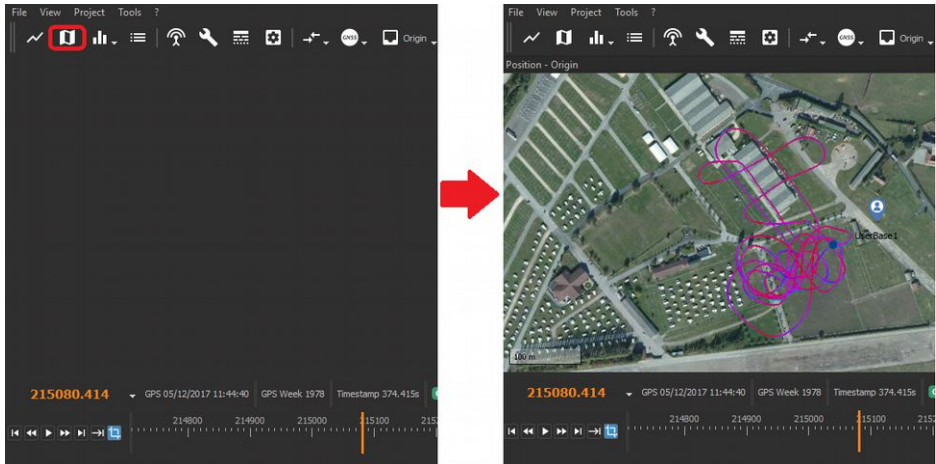
Select the data to be Post-Processed, configure the IMU model, import base station data, then enter the GNSS lever arms.



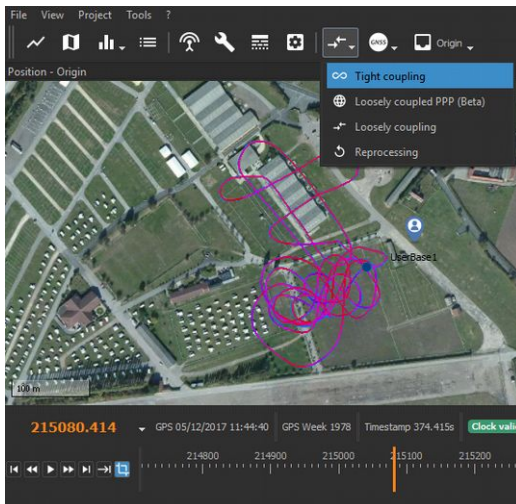
**Caution:** If the IMU alignment setting were already applied in the INS configuration, make sure to leave it to default (zero) in Qinertia, otherwise you will apply twice the alignment setting.

## Step 6: Process the tightly coupled solution

Now you finished creating your project you may start by displaying the 2D plot, this will show you the GNSS and real time fused trajectory on the map.



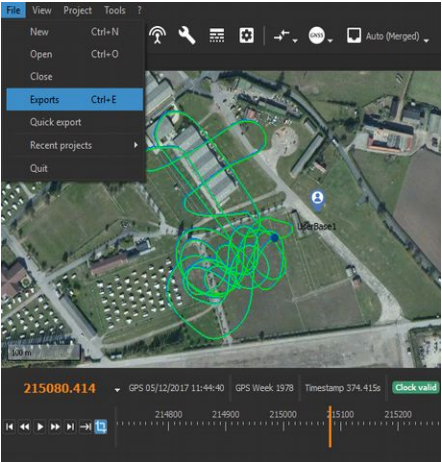
You can then press the Tight coupling option to launch the post-processing:



You will see on the time bar the forward and backward computation being realized at the same time, then the merge.

# Step 7: Export Data

When the Post-Processing is done, you may export the data in a customizable text format, in SBET compatible file or Google Earth KMZ file.



The export window will give you the option to create your own export profile, and export presets.

The export preset menu is extremely versatile and give you a true customizable export format.

