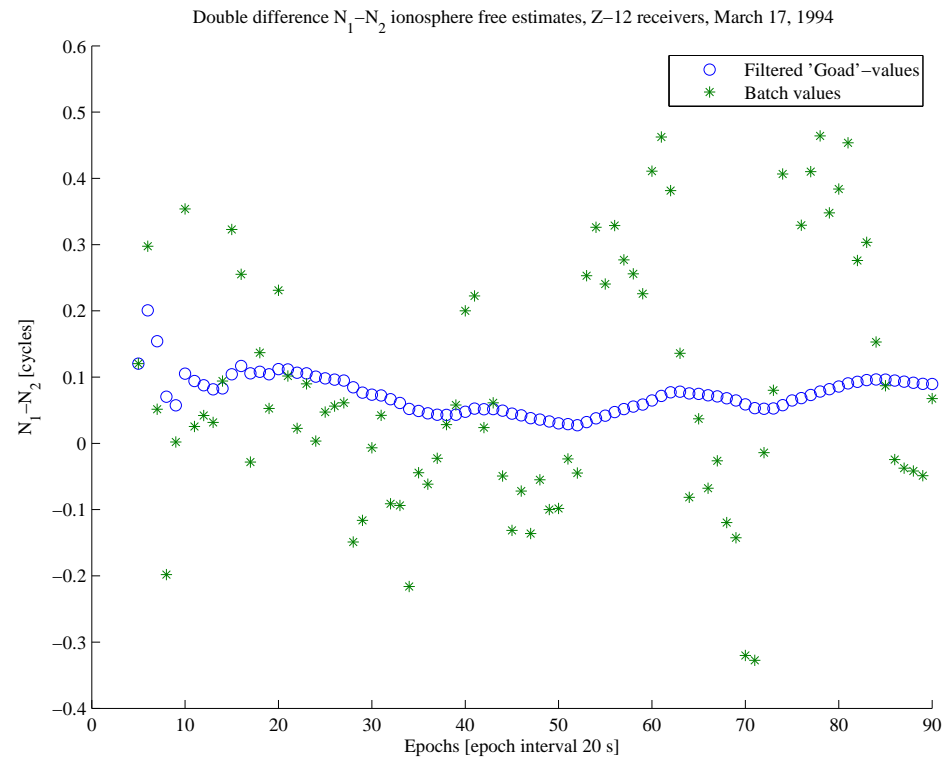


# Estimation of integer ambiguity for double differenced GPS pseudoranges



k\_dd3(2)



Copyright © 2011 by Kai Borre



# Smoothing

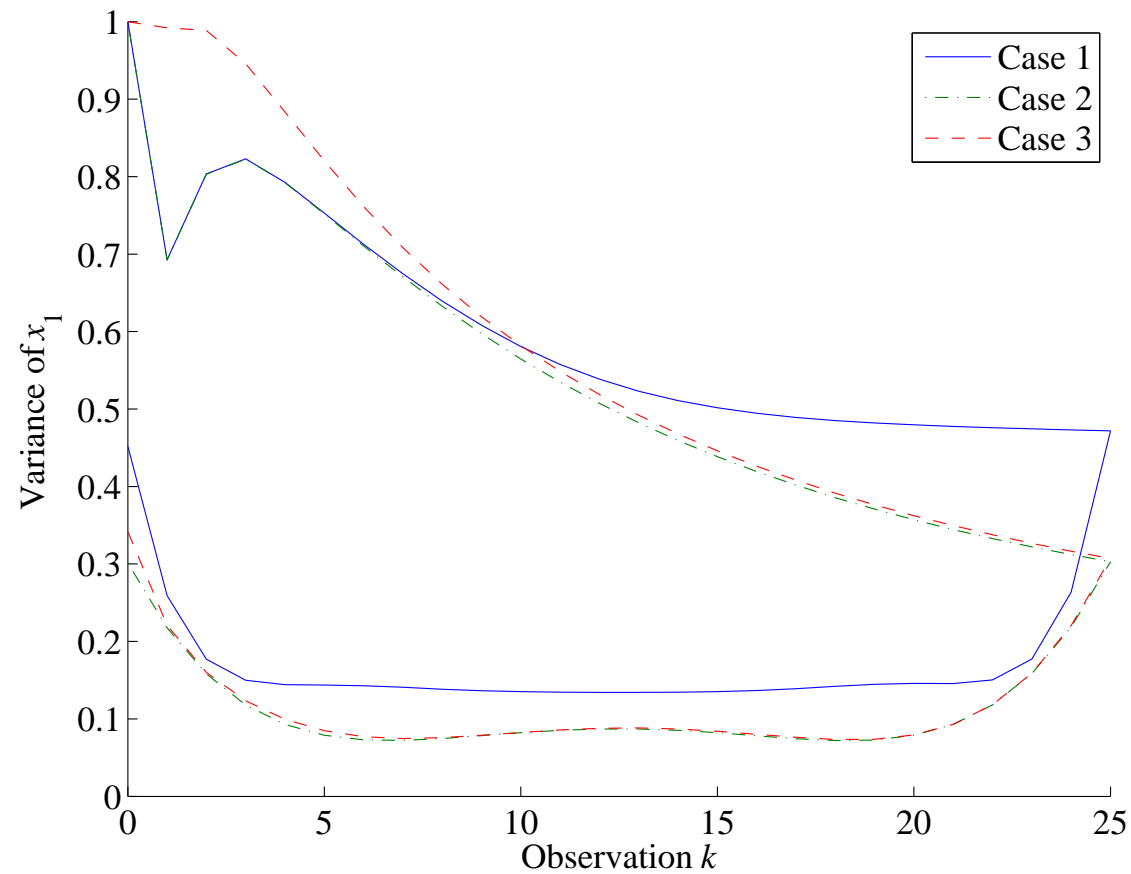
*Kai Borre*



Copyright © 2011 by Kai Borre



Smoothing with varying system noise  $\epsilon = 6.3 \times 10^{-3}$ ,  $\times 10^{-5}$ , and  $\times 10^{-3}$

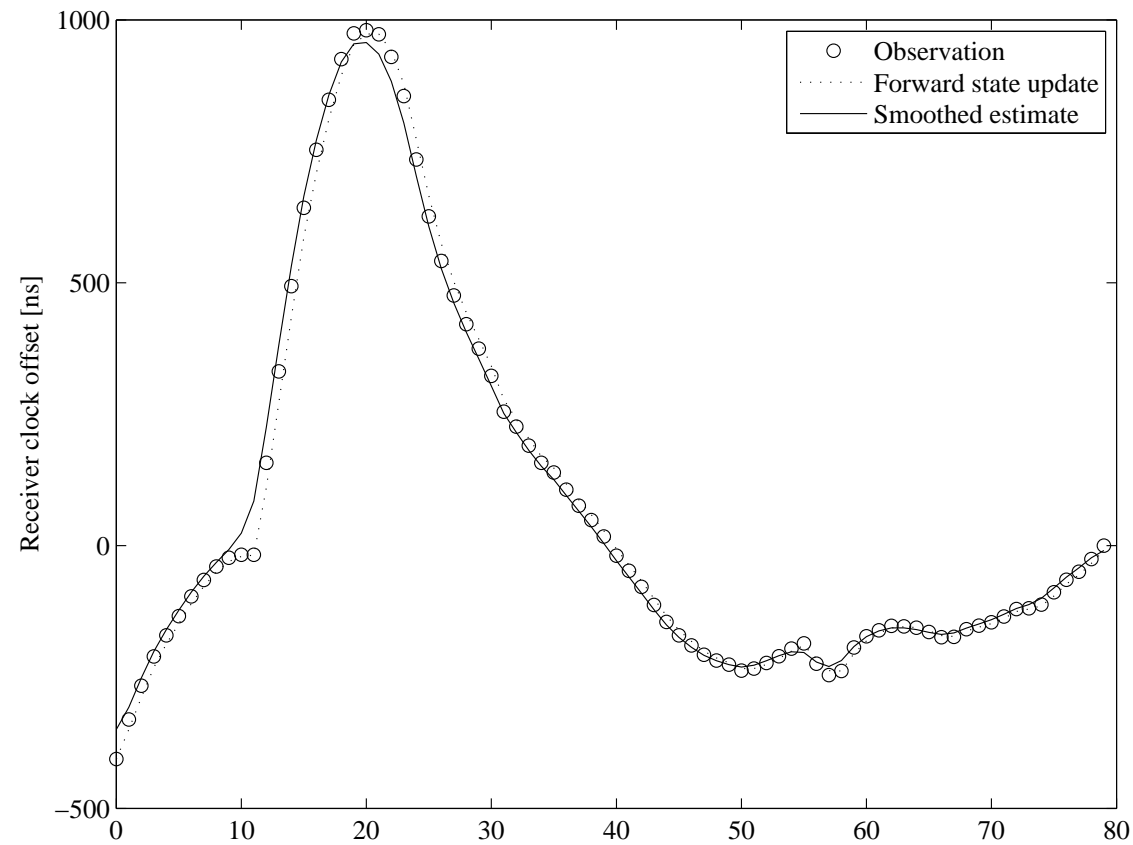


Copyright © 2011 by Kai Borre



rts

GPS receiver clock offset,  $\Sigma_e = 1$ ,  $\Sigma_\epsilon = 1$

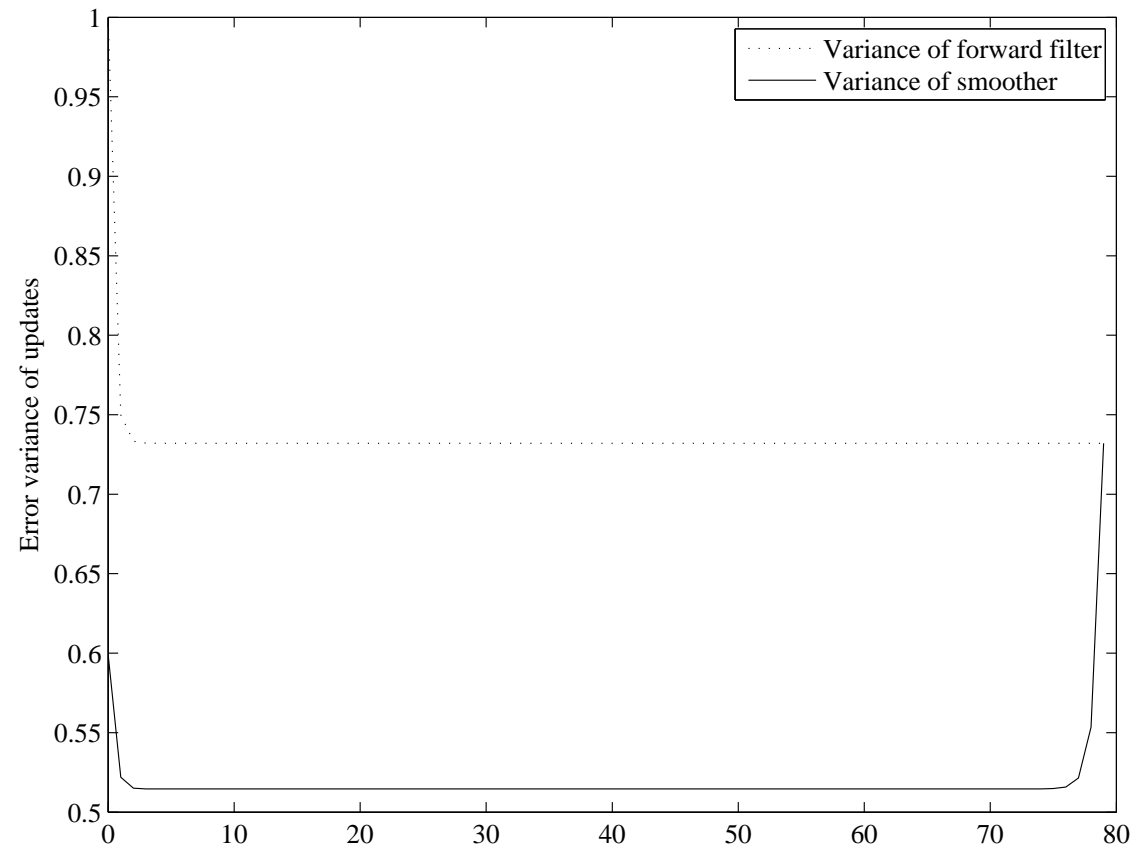


smoother(1,1)



Copyright © 2011 by Kai Borre

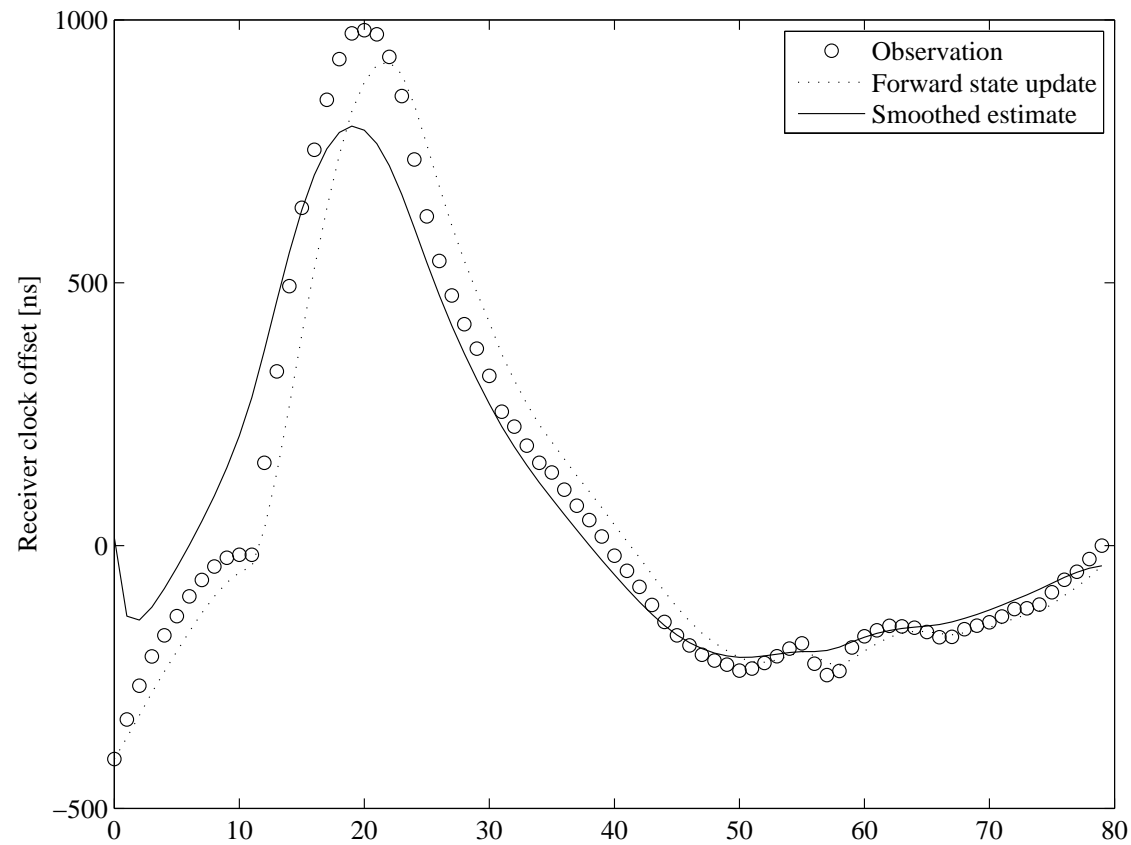




Copyright © 2011 by Kai Borre



GPS receiver clock offset,  $\Sigma_e = .1$ ,  $\Sigma_\epsilon = 1$

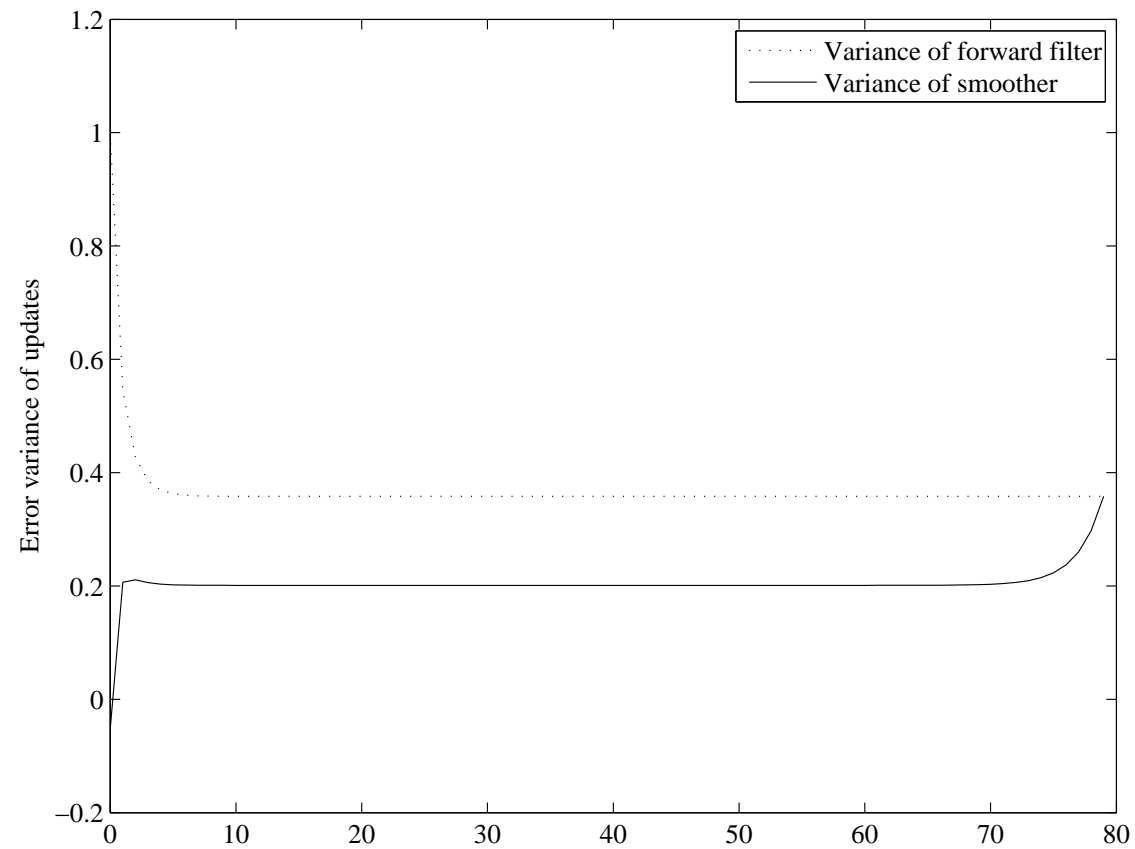


smoother(0.1,1)



Copyright © 2011 by Kai Borre





Copyright © 2011 by Kai Borre

