

4.2.10 GNSS Attitude Blocks

AttEuler	Number: 5938
	"OnChange" interval: default PVT output rate (see 4.1.8)

The `AttEuler` block contains the Euler angles (pitch, roll and heading) at the time specified in the `TOW` and `WNc` fields (in the receiver time frame).

Parameter	Type	Units	Do-Not-Use	Description
Sync1	c1			Block Header, see 4.1.1
Sync2	c1			
CRC	u2			
ID	u2			
Length	u2	1 byte		
TOW	u4	0.001 s	4294967295	Receiver time stamp, see 4.1.3
WNc	u2	1 week	65535	
NrSV	u1		255	The average over all antennas of the number of satellites currently included in the attitude calculations.
Error	u1			<p>Bit field providing error information. For each antenna baseline, two bits are used to provide error information:</p> <p>Bits 0-1: Error code for Main-Aux1 baseline: 0: No error 1: Not enough measurements 2: Reserved 3: Reserved</p> <p>Bits 2-3: Error code for Main-Aux2 baseline, same definition as bit 0-1. Bits 4-6: Reserved Bit 7: Set when GNSS-based attitude not requested by user. In that case, the other bits are all zero.</p>
Mode	u2			<p>Attitude mode code:</p> <p>0: No attitude 1: Heading, pitch (roll = 0), aux antenna positions obtained with float ambiguities 2: Heading, pitch (roll = 0), aux antenna positions obtained with fixed ambiguities 3: Heading, pitch, roll, aux antenna positions obtained with float ambiguities 4: Heading, pitch, roll, aux antenna positions obtained with fixed ambiguities</p>
Reserved	u2			Reserved for future use, to be ignored by decoding software
Heading	f4	1 degree	$-2 \cdot 10^{10}$	Heading
Pitch	f4	1 degree	$-2 \cdot 10^{10}$	Pitch
Roll	f4	1 degree	$-2 \cdot 10^{10}$	Roll
PitchDot	f4	1 degree / s	$-2 \cdot 10^{10}$	Rate of change of the pitch angle
RollDot	f4	1 degree / s	$-2 \cdot 10^{10}$	Rate of change of the roll angle
HeadingDot	f4	1 degree / s	$-2 \cdot 10^{10}$	Rate of change of the heading angle
Padding	u1[.]			Padding bytes, see 4.1.5