

# NOAA Ship THOMAS JEFFERSON Procedure Document

Procedure:

**Post Process GAMS**

Creation Date:

8/27/2020

Revision Date:

Software used:

POSPac

Procedure Number:

**TBD**

Approved:

**TBD**

# 1. Overview and Scope

How to post process GAMS.

## 2. Procedure Inputs and Outputs

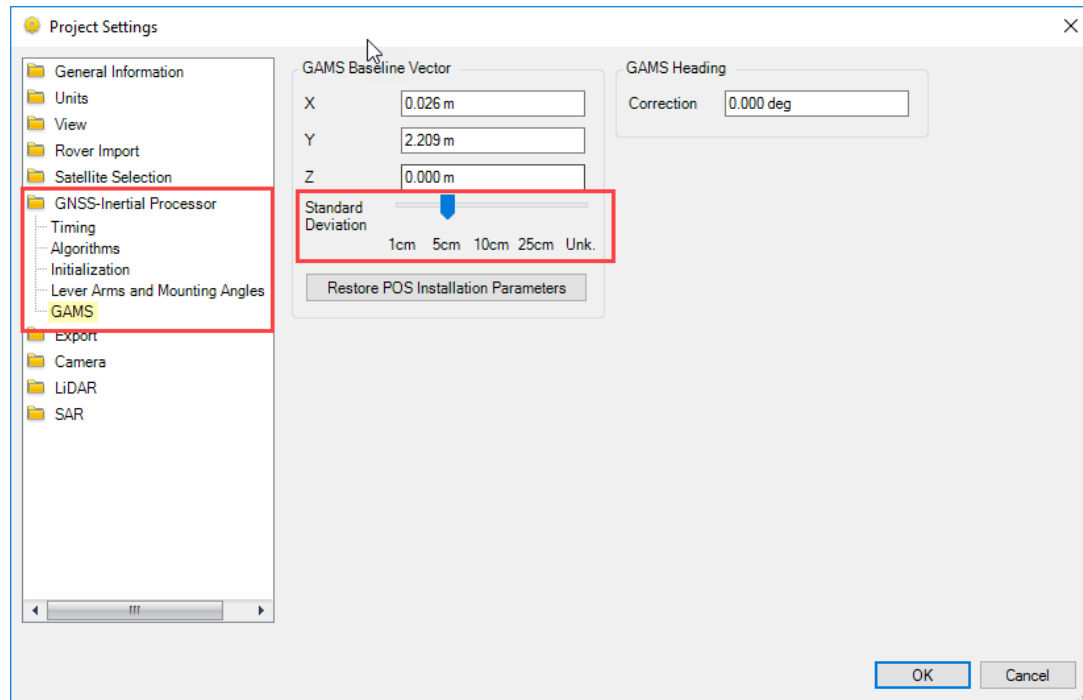
Inputs:

.000

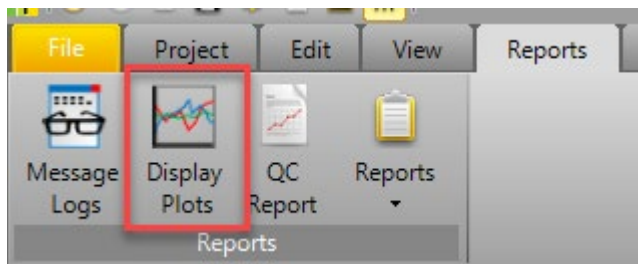
Outputs:

## 3. Procedure

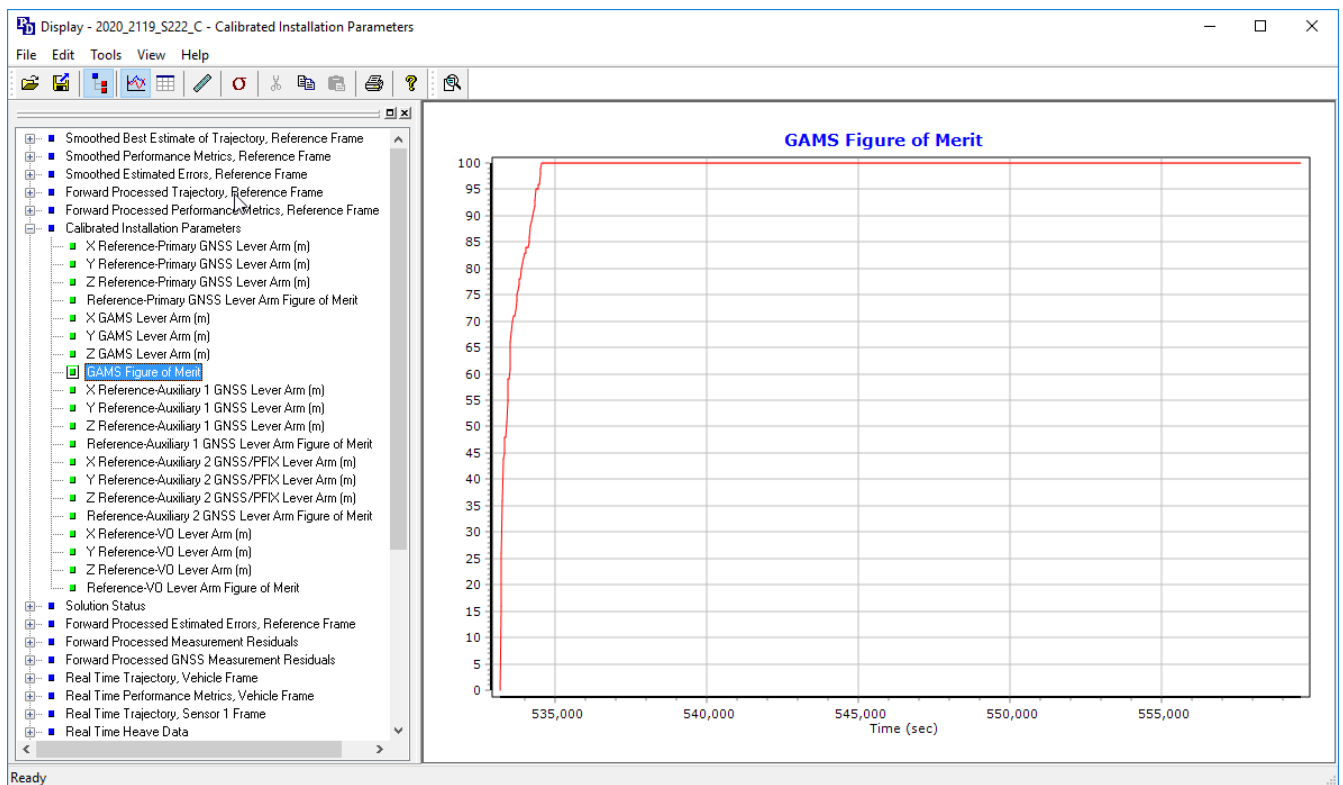
Process into POSpac as you normally would. Before you run the GNSS- Inertial Processor, go to Project Settings. Under the GNSS-Inertial Processor folder, select GAMS. Set the Standard Deviation to 5cm and click okay.



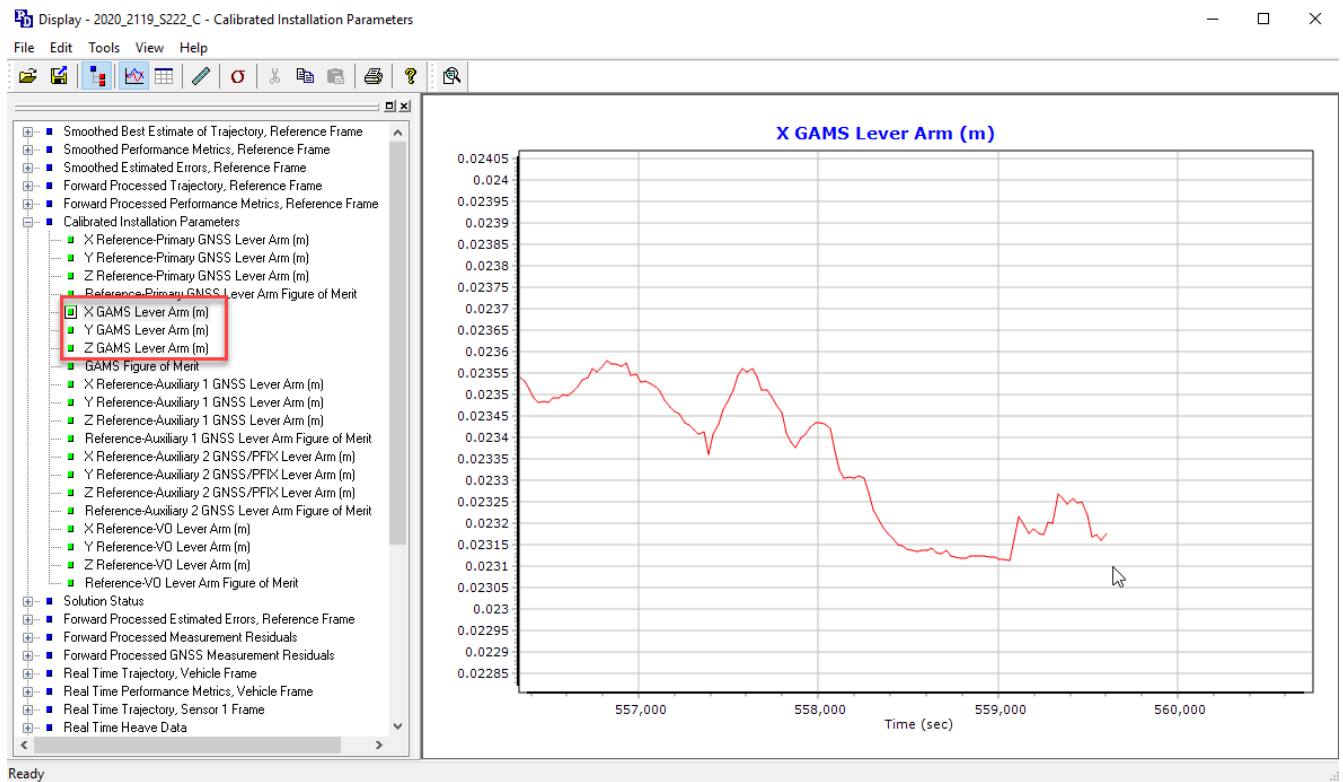
Run the GNSS-Inertial Processor for IN-Fusion PP-RTX. After you run the GNSS-Inertial Processor select the reports tab at the top of the program and select display plots.



With the display plot window open, select the drop down for Calibrated Installation Parameters. See if your GAMS' Figure of Merit is at 100. If it is not you should not use the calibrated values.



If it is, select the X GAMS Lever Arm, Zoom in on the last section of the chart on the right. This ending value is the calibrated value for X. Write down the values for X, Y, and Z.



After you have your values for X, Y, and Z, go back to the Project settings and enter these values into the GAMS Baseline Vector for each respective lever arm.

Project Settings

General Information  
Units  
View  
Rover Import  
Satellite Selection  
GNSS-Inertial Processor  
Timing  
Algorithms  
Initialization  
Lever Arms and Mounting Angles  
GAMS  
Export  
Camera  
LiDAR  
SAR

GAMS Baseline Vector

X 0.026 m  
Y 2.209 m  
Z 0.000 m

Standard Deviation  
1cm 5cm 10cm 25cm Unk.

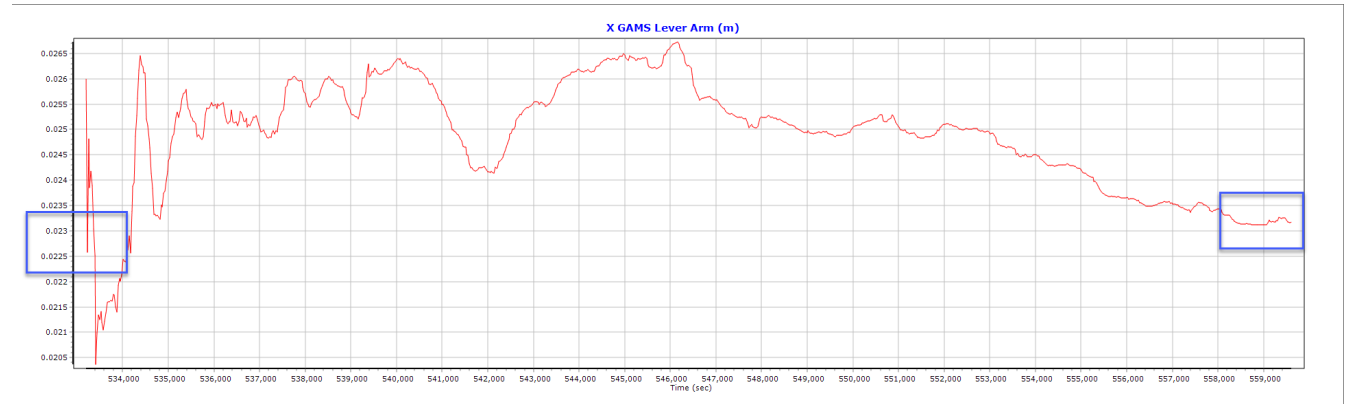
Restore POS Installation Parameters

GAMS Heading  
Correction 0.000 deg

OK Cancel

Now rerun GNSS-Inertial Processor.

Repeat these steps till the starting lever arm is close to the ending calibrated value.



After finding your final calibrated values, Input these values into POS for the GAMS Baseline Vector.

## 4. References

N/A