



**ROYAL INSTITUTE  
OF TECHNOLOGY**

# **GPS single point positioning algorithm**

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# 1 Computation of receiver's position

This paper describes the computation of the position of a GPS receiver based on L1 pseudorange observations, here denoted by  $P$ . The algorithm is summarised in Table 1.

The GPS satellites continuously transmit signals on two bands: L1 and L2. Usually, only L1 is used for navigation purposes. There are three data streams modulated on L1: C/A ranging code, P ranging code and navigation message. The receiver correlates the received and generated ranging codes by shifting the generated ones with respect to the received ones. The amount of the shift is a measure of the travel time of the signal from satellite to the receiver. The travel time derived from the code correlation multiplied by the speed of light is called pseudorange. The mathematical definition of the pseudorange is given by the following equation:

$$P_A^s(\tilde{t}_A) = (\tilde{t}_A - \tilde{t}^s)c \quad (1)$$

where

|                      |  |
|----------------------|--|
| $P_A^s(\tilde{t}_A)$ | pseudorange measured at time $\tilde{t}_A$ by receiver A to satellite s  |
| $\tilde{t}_A$        | nominal time of the signal reception measured by the clock of receiver A |
| $\tilde{t}^s$        | nominal time of signal transmission measured by the clock of satellite s |
| $c$                  | speed of light (see the value on page 9)                                 |

It is evident, that the pseudorange is directly affected by the satellite and receiver clock errors. The clock errors are defined by the following equations:

$$\begin{aligned} t_A &= \tilde{t}_A - \delta t_A \\ t^s &= \tilde{t}^s - \delta t^s \end{aligned} \quad (2)$$

where

|              |  |
|--------------|--|
| $\delta t_A$ | receiver clock error                             |
| $\delta t^s$ | satellite clock error                            |
| $t_A$        | system time of the signal reception              |
| $t^s$        | system time of the signal transmission           |
| $c$          | speed of light, numerical value is in Section 5. |

By introducing (2) into Equation (1), we get:

$$P_A^s(\tilde{t}_A) = \rho_A^s(t_A) + c \delta t_A - c \delta t^s \quad (3)$$

where  $\rho_A^s(t_A)$  is geometric distance between receiver A and satellite s at time  $t_A$  (also called topocentric distance):

$$\rho_A^s(t_A) = c(t_A - t^s) = c\Delta t_A^s \quad (4)$$

Where  $\Delta t_A^s$  is signal propagation time, which can be computed with sufficient accuracy by Equation (13).

Since the system (true) time  $t_A$  is unknown, the topocentric distance must be linearised around the known nominal receiver time  $\tilde{t}_A$ :

$$\rho_A^s(t_A) = \rho_A^s(\tilde{t}_A) - \dot{\rho}_A^s(\tilde{t}_A) \delta t_A \quad (5)$$

The second term in right side of equation (5) is at most about 0.8 m, therefore it can be neglected in case of code single point positioning (other error sources are larger).

We can relate the distance to the coordinates using Pythagoras' Theorem as follows:

$$\rho_A^s(\tilde{t}_A) = \sqrt{(X^s - x_A)^2 + (Y^s - y_A)^2 + (Z^s - z_A)^2} \quad (6)$$

where

$X^s, Y^s, Z^s$  Cartesian coordinates of satellite  $s$  in WGS84

$x_A, y_A, z_A$  Cartesian coordinates of receiver A expressed in rotated reference frame, due to the rotation of the Earth during the signal's travel time.

The coordinates are related to WGS84 coordinates by:

$$\begin{aligned} x_A &= X_A - \dot{\Omega}_e Y_A \Delta t_A^s \\ y_A &= Y_A + \dot{\Omega}_e X_A \Delta t_A^s \\ z_A &= Z_A \end{aligned} \quad (7)$$

$X^A, Y^A, Z^A$  are WGS84 coordinates of the receiver, which are to be computed and  $\dot{\Omega}_e$  is the rotation rate of the Earth. Looking at Equations (3) - (7), we can see that there are four unknowns, namely three receiver coordinates  $X^A, Y^A, Z^A$  and receiver clock error  $\delta t_A$ . The satellite coordinates  $X^s, Y^s, Z^s$  can be computed using orbit parameters, satellite clock error  $\delta t^s$  can be computed using clock polynomial coefficients transmitted to the user in the navigation message, and the pseudorange  $P_A^s(\tilde{t}_A)$  is measured by the GPS receiver.

Taking into account the tropospheric  $T_A^s(\tilde{t}_A)$  and ionospheric  $I_A^s(\tilde{t}_A)$  delays as well as Equation (5) neglecting term with  $\delta t_A$ , the observation equation (3) can be written as:

$$P_A^s(\tilde{t}_A) = \rho_A^s(\tilde{t}_A) + c \delta t_A - c \delta t_{L1}^s + I_A^s(\tilde{t}_A) + T_A^s(\tilde{t}_A) \quad (8)$$

If we insert Equation (7) into (6) and then linearise it using the Taylor's expansion, and neglecting higher order terms, we get:

$$\rho_A^s(\tilde{t}_A) = \rho_{A0}^s(\tilde{t}_A) + \frac{\partial \rho_{A0}^s(\tilde{t}_A)}{\partial X_{A0}} \Delta X + \frac{\partial \rho_{A0}^s(\tilde{t}_A)}{\partial Y_{A0}} \Delta Y + \frac{\partial \rho_{A0}^s(\tilde{t}_A)}{\partial Z_{A0}} \Delta Z \quad (9)$$

$$\begin{aligned}
\frac{\partial \rho_{A0}^s(t_A)}{\partial X_{A0}} &= a_X^s = -\frac{X^s - X_{A0} + Y^s \dot{\Omega}_e \Delta t_A^s - X_{A0} \dot{\Omega}_e^2 \Delta t_A^{s^2}}{\rho_{A0}^s} \\
\frac{\partial \rho_{A0}^s(t_A)}{\partial Y_{A0}} &= a_Y^s = -\frac{Y^s - Y_{A0} - X^s \dot{\Omega}_e \Delta t_A^s - Y_{A0} \dot{\Omega}_e^2 \Delta t_A^{s^2}}{\rho_{A0}^s} \\
\frac{\partial \rho_{A0}^s(t_k)}{\partial Z_{A0}} &= a_Z^s = -\frac{Z^s - Z_{A0}}{\rho_{A0}^s}
\end{aligned} \tag{10}$$

where

$$\rho_{A0}^s(\tilde{t}_A) = \sqrt{(X^s - X_{A0} + \dot{\Omega}_e Y_{A0} \Delta t_A^s)^2 + (Y^s - Y_{A0} - \dot{\Omega}_e X_{A0} \Delta t_A^s)^2 + (Z^s - Z_{A0})^2} \tag{11}$$

The terms containing  $\Delta t_A^s$  in Equations (10) are negligible, so the coefficients can be computed by simplified equations:

$$\begin{aligned}
\frac{\partial \rho_{A0}^s(t_A)}{\partial X_{A0}} &= a_X^s = -\frac{X^s - X_{A0}}{\rho_{A0}^s} \\
\frac{\partial \rho_{A0}^s(t_A)}{\partial Y_{A0}} &= a_Y^s = -\frac{Y^s - Y_{A0}}{\rho_{A0}^s} \\
\frac{\partial \rho_{A0}^s(t_k)}{\partial Z_{A0}} &= a_Z^s = -\frac{Z^s - Z_{A0}}{\rho_{A0}^s}
\end{aligned} \tag{12}$$

$X_{A0}$ ,  $Y_{A0}$  and  $Z_{A0}$  are approximate receiver coordinates,  $\Delta X$ ,  $\Delta Y$ ,  $\Delta Z$  are unknown corrections to the approximate coordinates and  $\Delta t_A^s$  is signal propagation time that can be computed with sufficient accuracy by:

$$\Delta t_A^s = \frac{P_A^s(\tilde{t}_A)}{c} \tag{13}$$

$\dot{\Omega}_e$  is the rotation rate of the Earth, numerically given in Section 5.

$X^s$ ,  $Y^s$ ,  $Z^s$  are WGS84 coordinates of satellite  $s$  computed at time of signal transmission  $t^s$ . The nominal transmission time  $\tilde{t}^s$  is computed by:

$$\tilde{t}^s = \tilde{t}_A - \frac{P_A^s(\tilde{t}_A)}{c} \tag{14}$$

The system transmission time  $t^s$  is computed as:

$$t^s = \tilde{t}^s - \delta t_{L1}^s \tag{15}$$

Where  $\delta t_{L1}^s$  is satellite clock correction computed by Equation (26).

The observation equation (8) can be then rewritten as:

$$P_A^s(\tilde{t}_A) - \rho_{A0}^s(\tilde{t}_A) + c \delta t_{L1}^s - I_A^s(\tilde{t}_A) - T_A^s(\tilde{t}_A) = a_X^s \Delta X + a_Y^s \Delta Y + a_Z^s \Delta Z + c \delta t_A \quad (16)$$

The left side of this equation contains the terms that are known (measured and computed), while the right side contains terms with unknown parameters  $\Delta X$ ,  $\Delta Y$ ,  $\Delta Z$  and  $\delta t_A$ . These parameters can be solved if at least 4 measurements are available. The parameters are solved by the least-squares (LSQ) method. This method is most conveniently expressed in matrix notation. Observation equations – system of equations to be solved:

$$\mathbf{L} - \mathbf{v} = \mathbf{A}\mathbf{X} \quad (17)$$

where  $\mathbf{v}$  is vector of unknown residuals (random errors of measurements). LSQ solution of (17):

$$\begin{aligned} \hat{\mathbf{X}} &= \mathbf{Q}_X \mathbf{A}^T \mathbf{L} \\ \mathbf{Q}_X &= (\mathbf{A}^T \mathbf{A})^{-1} \end{aligned} \quad (18)$$

$\mathbf{L}$  is the vector with  $n$  elements, where  $n$  is the number of observed satellites:

$$\mathbf{L} = \begin{bmatrix} P_A^1(\tilde{t}_A) - \rho_{A0}^1(\tilde{t}_A) + c \delta t_{L1}^1 - I_A^1(\tilde{t}_A) - T_A^1(\tilde{t}_A) \\ \vdots \\ P_A^n(\tilde{t}_A) - \rho_{A0}^n(\tilde{t}_A) + c \delta t_{L1}^n - I_A^n(\tilde{t}_A) - T_A^n(\tilde{t}_A) \end{bmatrix} \quad (19)$$

$\mathbf{A}$  is the design matrix containing the coefficients at unknown parameters. Its size is  $n \times 4$ :

$$\mathbf{A} = \begin{bmatrix} a_X^1 & a_Y^1 & a_Z^1 & 1 \\ \vdots & \vdots & \vdots & \vdots \\ a_X^n & a_Y^n & a_Z^n & 1 \end{bmatrix} \quad (20)$$

$\mathbf{X}$  is the vector of the four unknowns:

$$\mathbf{X} = [\Delta X \quad \Delta Y \quad \Delta Z \quad c \delta t_A]^T \quad (21)$$

The estimated coordinates of the receiver are finally computed by:

$$\begin{aligned} X_A &= X_{A0} + \Delta X \\ Y_A &= Y_{A0} + \Delta Y \\ Z_A &= Z_{A0} + \Delta Z \end{aligned} \quad (22)$$

Please note that we estimate the receiver clock error multiplied by the velocity of light ( $c\delta t_A$ ), rather than clock error ( $\delta t_A$ ), to get better numerical stability of the solution.

Finally, we compute the standard uncertainties (standard deviations) of the estimated parameters as

$$\begin{aligned} s_X &= s_0 \sqrt{Q_{x(1,1)}} \\ s_Y &= s_0 \sqrt{Q_{x(2,2)}} \\ s_Z &= s_0 \sqrt{Q_{x(3,3)}} \\ s_{cdt} &= s_0 \sqrt{Q_{x(4,4)}} \end{aligned} \quad (23)$$

where

$$\begin{aligned} s_0 &= \sqrt{\frac{\mathbf{v}^T \mathbf{v}}{n - k}} \\ \mathbf{v} &= \mathbf{A} \hat{\mathbf{X}} - \mathbf{L} \end{aligned} \quad (24)$$

$n$  – number of satellites,  $k$  – number of parameters ( $k = 4$ ).

PDOP can be estimated by  $PDOP = \sqrt{Q_{x(1,1)} + Q_{x(2,2)} + Q_{x(3,3)}}$

Table 1. Algorithm for computation of receiver's position.

- |  |
|--|
| <ol style="list-style-type: none"> <li>1. Compute signal propagation time by (13).</li> <li>2. Compute signal transmission time <math>\tilde{t}^s</math> by (14).</li> <li>3. Compute satellite clock correction <math>\delta t_{Li}^s</math> by (26) and (27), neglect <math>\Delta t_r</math>.</li> <li>4. Compute <math>t^s</math> by (15) using the correction from the step 3.</li> <li>5. Compute eccentric anomaly (Table 2 - line 4-8)</li> <li>6. Compute <math>\Delta t_r</math> by (28), <math>\Delta t_{sv}</math> by (27), <math>\delta t_{Li}^s</math> by (26) and <math>t^s</math> by (15).</li> <li>7. Compute satellite coordinates <math>X^s, Y^s, Z^s</math>, for time <math>t^s</math> - Table 2 (line 4-19). Update the eccentric anomaly computed in step 5.</li> <li>8. Compute satellite clock correction <math>\delta t_{Li}^s</math> by (26) - (29) using the updated eccentric anomaly.</li> <li>9. Compute tropospheric correction <math>T_A^s(\tilde{t}_A)</math>.</li> <li>10. Compute ionospheric correction <math>I_A^s(\tilde{t}_A)</math>.</li> <li>11. Compute approximate distance <math>\rho_{A0}^s(\tilde{t}_A)</math> by (11).</li> <li>12. Compute elements of vector <math>\mathbf{L}</math> (19).</li> <li>13. Compute elements of matrix <math>\mathbf{A}</math> (20); <math>a_x^s, a_y^s, a_z^s</math> by (12).</li> <li>14. Estimate unknown parameters by (18).</li> <li>15. Update receiver coordinates by (22).</li> <li>16. Repeat steps 11 – 16 until the solution has converged. The solution has converged if the following condition is fulfilled: <math>\left  (\mathbf{v}^T \mathbf{v})_i - (\mathbf{v}^T \mathbf{v})_{i-1} \right  &lt; \varepsilon</math>, where <math>\varepsilon</math> is a small number and depends on the numerical accuracy, <math>\varepsilon = 1e-5</math> should suffice to preserve mm numerical precision of the computed coordinates; <math>i</math> is iteration number. The vector <math>\mathbf{v}</math> is computed after step 13 by Equation (17).</li> </ol> |
|--|

## 2 Calculation of satellite coordinates

This section describes the computation of WGS84 coordinates of a GPS satellite for time of signal transmission  $t^s$ , computed by Equation (14) and (2). The coordinates are computed by the equations listed in Table 2. The necessary orbital parameters are found in the RINEX navigation file – see chapter 4.

During the coordinate computation, the Kepler's equation for eccentric anomaly must be solved. The following iterative solution is applied:

$$\begin{aligned} E_0 &= M_k \\ E_i &= M_k + e \sin E_{i-1}, \quad i = 1, 2, 3, \dots \end{aligned} \quad (25)$$

The iteration can be stopped if  $|E_i - E_{i-1}| < \varepsilon$ , where  $\varepsilon$  is a small number. We recommend  $\varepsilon = 1e-13$ . Usually, 4 or 5 iterations suffice.

## 3 Satellite clock correction computation

The satellite clock correction  $\delta t_{L1}^s$  is needed for receiver position computation (in Equation (19)). For epoch  $\tilde{t}^s$ , it is computed by the following equation:

$$\delta t_{L1}^s = \Delta t_{SV} - T_{GD} \quad (26)$$

where

$$\Delta t_{SV} = a_{f0} + a_{f1} (\tilde{t}^s - t_{oc}) + a_{f2} (\tilde{t}^s - t_{oc})^2 + \Delta t_r \quad (27)$$

$\Delta t_r$  is the relativistic correction given by:

$$\Delta t_r = Fe\sqrt{A} \sin E_k \quad (28)$$

where  $F$  is a constant:

$$F = -4.442807633e - 10 \text{ s/m}^{1/2} \quad (29)$$

$e$  and  $A$  are orbit parameters and  $E_k$  is eccentric anomaly computed in course of satellite coordinates computation (see Table 2). Please note that  $(\tilde{t}^s - t_{oc})$  is the time difference expressed in seconds.

Table 2. Computation of satellite coordinates from orbital parameters. Source: Interface control document ICD-GPS-200.

|    |   |  |
|----|---|--|
| 1  | $\mu = 3.986005 \times 10^{14} \text{ m}^3/\text{s}^2$  | Earth' universal gravitational parameter   |
| 2  | $\dot{\Omega}_e = 7.2921151467 \times 10^{-5} \text{ rad/s}$  | Earth' rotation rate   |
| 3  | $A = (\sqrt{A})^2$  | Semi-major axis  |
| 4  | $n_0 = \sqrt{\frac{\mu}{A^3}}$  | Computed mean motion   |
| 5  | $t_k = t^s - t_{oe}$<br>$t_k = \begin{cases} t_k - 604800 & \text{if } t_k > 302400 \\ t_k + 604800 & \text{if } t_k < -302400 \\ t_k & \text{otherwise} \end{cases}$ | Time from ephemeris reference epoch  |
| 6  | $n = n_0 + \Delta n$  | Corrected mean motion  |
| 7  | $M_k = M_0 + n t_k$   | Mean anomaly   |
| 8  | $E_k = M_k + e \sin E_k$  | Kepler's equation for eccentric anomaly. Solution by Eq. (25)                                  |
| 9  | $\sin v_k = \frac{\sqrt{1-e^2} \sin E_k}{1 - e \cos E_k}$<br>$\cos v_k = \frac{\cos E_k - e}{1 - e \cos E_k}$   | True anomaly. Correct quadrant of $v_k$ must be determined. We recommend using atan2 function. |
| 10 | $\Phi_k = v_k + \omega$   | Argument of latitude   |
| 11 | $\delta u_k = c_{us} \sin 2\Phi_k + c_{uc} \cos 2\Phi_k$  | Argument of latitude correction  |
| 12 | $\delta r_k = c_{rs} \sin 2\Phi_k + c_{rc} \cos 2\Phi_k$  | Radius correction  |
| 13 | $\delta i_k = c_{is} \sin 2\Phi_k + c_{ic} \cos 2\Phi_k$  | Inclination correction   |
| 14 | $u_k = \Phi_k + \delta u_k$   | Corrected argument of latitude   |
| 15 | $r_k = A(1 - e \cos E_k) + \delta r_k$  | Corrected radius   |
| 16 | $i_k = i_0 + \delta i_k + (\text{IDOT}) t_k$  | Corrected inclination  |
| 17 | $x'_k = r_k \cos u_k$<br>$y'_k = r_k \sin u_k$  | Position in orbital plane  |
| 18 | $\Omega_k = \Omega_0 + (\dot{\Omega} - \dot{\Omega}_e) t_k - \dot{\Omega}_e t_{oe}$   | Corrected longitude of ascending node  |
| 19 | $x_k = x'_k \cos \Omega_k - y'_k \cos i_k \sin \Omega_k$<br>$y_k = x'_k \sin \Omega_k + y'_k \cos i_k \cos \Omega_k$<br>$z_k = y'_k \sin i_k$                         | WGS84 Cartesian coordinates, ( $X^s = x_k$ , $Y^s = y_k$ , $Z^s = z_k$ )                       |



## 4 Identification of orbit parameters in RINEX format

RINEX format is defined in [2]. There are several types of RINEX files: observation, meteorological, message and navigation files. Only navigation files are relevant in this report. The name of a GPS navigation file is usually in form *ssssdddf.yyN* where

|             |                                     |
|-------------|-------------------------------------|
| <i>ssss</i> | 4-character station name designator |
| <i>ddd</i>  | day of the year of first record     |
| <i>f</i>    | file sequence number within day     |
| <i>yy</i>   | year                                |
| <i>N</i>    | stands for “navigation”             |

If  $f = 0$ , file contains all the existing data of the current day.

Navigation file is a text file consisting of two parts: header and data records. The complete description of header is given in Table 5. Data records follow immediately after the header. One record contains data for one satellite and one reference epoch. Each record consists of 8 lines. The first line contains satellite number (PRN), reference epoch of clock parameters, and clock polynomial parameters. Lines 2 - 8 contain four numbers each. The meaning of the numbers is described in Table 4. Format of numbers is described by FORTRAN symbolism. The meaning of used symbols:

|       |  |
|-------|--|
| 1X    | one space  |
| F9.2  | floating number expressed by 9 digits (including decimal point and sign), 2 of them are reserved for decimals          |
| A20   | 20 characters long string  |
| D12.4 | double-precision number expressed by 12 digits (including decimal point and sign), 4 of them are reserved for decimals |
| I6    | integer, six digits long   |

Number before the type specifier (X, F, D, A, I) specifies number of repetitions. For example 4D12.4 specifies 4 double-precision numbers, each of them 12 digits long with four decimals.

## 5 Constants

The following constants are adopted by GPS exactly with given number of decimals.

Table 3. Constants according to the GPS interface document [1]

| Constant         | Numerical value               | Unit                    |
|------------------|-------------------------------|-------------------------|
| $c$              | 299792458                     | m/s                     |
| $\pi$            | 3.1415926535898               |                         |
| $\mu$            | $3.986005 \times 10^{14}$     | $\text{m}^3/\text{s}^2$ |
| $\dot{\Omega}_e$ | $7.2921151467 \times 10^{-5}$ | rad/s                   |

Table 4. GPS navigation message file - data record description

| LINE OF RECORD | DESCRIPTION   | FORMAT  |
|----------------|---|---|
| 1              | Satellite PRN number<br>Epoch: $t_{oc}$ - Time of Clock<br>year (2 digits)<br>month<br>day<br>hour<br>minute<br>second<br>SV clock bias $a_{f0}$<br>SV clock drift $a_{f1}$<br>SV clock drift rate $a_{f2}$ | I2,<br><br>1X, I2<br>1X, I2,<br>1X, I2,<br>1X, I2,<br>1X, I2,<br>F5.1<br>D19.12<br>D19.12<br>D19.12 |
| 2              | IODE<br>$C_{rs}$<br>$\Delta n$<br>$M_0$   | 3X, D19.12<br>D19.12<br>D19.12<br>D19.12  |
| 3              | $C_{uc}$<br>$e$<br>$C_{us}$<br>$\sqrt{A}$   | 3X, D19.12<br>D19.12<br>D19.12<br>D19.12  |
| 4              | $t_{oe}$<br>$C_{ic}$<br>$(\text{OMEGA})_0, \Omega_0$<br>$C_{is}$  | 3X, D19.12<br>D19.12<br>D19.12<br>D19.12  |
| 5              | $i_0$<br>$C_{rc}$<br>$\omega$<br>OMEGADOT, $\dot{\Omega}$   | 3X, D19.12<br>D19.12<br>D19.12<br>D19.12  |
| 6              | IDOT<br>Code on L2<br>Week No. (to go with $t_{oe}$ )<br>L2 P data flag   | 3X, D19.12<br>D19.12<br>D19.12<br>D19.12  |
| 7              | SV accuracy<br>SV health<br>$T_{GD}$<br>IODC  | 3X, D19.12<br>D19.12<br>D19.12<br>D19.12  |
| 8              | Transmission time of message<br>Fit interval (Zero if not known)<br>Spare<br>Spare  | 3X, D19.12<br>D19.12<br>D19.12<br>D19.12  |

Table 5. GPS navigation message file - header section description, [2]

| HEADER LABEL<br>(Columns 61-80) | DESCRIPTION  | FORMAT                |
|---------------------------------|--|-----------------------|
| RINEX VERSION / TYPE            | - Format version (2.10)<br>- File type ('N' for Navigation data)   | F9.2, 11X,<br>A1, 19X |
| PGM / RUN BY / DATE             | - Name of program creating current file<br>- Name of agency creating current file<br>- Date of file creation   | A20,<br>A20,<br>A20   |
| COMMENT                         | Comment line(s)  | A60                   |
| ION ALPHA                       | Ionosphere parameters $\alpha_0 - \alpha_3$  | 2X, 4D12.4            |
| ION BETA                        | Ionosphere parameters $\beta_0 - \beta_3$  | 2X, 4D12.4            |
| DELTA-UTC: A0,A1,T,W            | Almanac parameters to compute time in UTC<br>A0, A1: terms of polynomial<br>T : reference time for UTC data<br>W : UTC reference week number.<br>Continuous number, not mod(1024)! | 3X, 2D19.12,<br>2I9   |
| LEAP SECONDS                    | Delta time due to leap seconds   | I6                    |
| END OF HEADER                   | Last record in the header section.   | 60X                   |

|              |                             |                          |
|--------------|-----------------------------|--------------------------|
| Satellite nr | Year month day hour min sec | OMEGADOT, $\dot{\Omega}$ |
| 2            | 04 2 2 2 0 0.0              | -7.938902115710D-09      |

```

2.677510492500D-04-6.821210263300D-12 0.000000000000D+00
2.310000000000D+02 1.465625000000D+01 5.271290999000D-09-2.145798944750D+00
9.164214134220D-07 2.332063857470D-02 5.649402737620D-06 5.153571390150D+03
9.360000000000D+04 3.650784492490D-07 7.137554984610D-01 7.823109626770D-08
9.323963691140D-01 2.492500000000D+02-1.713391849830D+00-7.938902115710D-09
3.907305612110D-10 0.000000000000D+00 1.256000000000D+03 0.000000000000D+00
2.800000000000D+00 0.000000000000D+00-1.862645149230D-09 2.310000000000D+02
8.997000000000D+04

```

Table 6. Example of parameter identification in RINEX navigation file

```

2.10      OBSERVATION DATA      G (GPS)      RINEX VERSION / TYPE
teqc 2002Mar14      20040202 02:07:05UTC      PGM / RUN BY / DATE
.OU0.0      MARKER NAME
108638.0      MARKER NUMBER
SWEPOS      LMU      OBSERVER / AGENCY
201      ASHTECH UZ-12      UFB5      REC # / TYPE / VERS
486      ASH700936D_M      OSOD      ANT # / TYPE
3104219.4530  998383.9820  5463290.5080      APPROX POSITION XYZ
0.0710      0.0000      0.0000      ANTENNA: DELTA H/E/N
1 1      WAVELENGTH FACT L1/2
7 C1 L1 L2 P1 P2 D1 D2      # / TYPES OF OBSERV
15.0000      INTERVAL
Forced Modulo Decimation to 15 seconds      COMMENT
2004 2 2 1 0 0.0000000 0 12G24G13G 8G21G29G26G10G17G 2G28G 3G27      TIME OF FIRST OBS
2004 4 1 59      GPS      TIME OF LAST OBS
Y$Win2000|IAx86-PII|bcc3      GPS      COMMENT
teqc 2002Mar14      02 02:07:00UTC      COMMENT
IMoS GFileSrv 3.32 LMU      2004      COMMENT
END OF HEADER

04 2 2 1 0 0.0000000 0 12G24G13G 8G21G29G26G10G17G 2G28G 3G27
25001257.939 3 -3240782.381 3 -2477390.27041 25001256.67943 25001263.55241
-3326.175 -2591.814
23106629.672 3 -12188598.444 3 -9438884.30442 23106630.26943 23106632.40442
-3249.560 -2532.122
20664230.640 4 -27083620.911 4 -21043552.60142 20664230.28544 20664233.24942
1668.628 1300.232
24835458.607 3 -1852700.687 3 -1409814.31741 24835459.14243 24835461.18641
2256.893 1758.620

```

Table 7. Example of observation identification in RINEX observation file.

number of satellites  
for the epoch  
followed by list of  
them

P1 code pseudorange  
towards satellite 13

## 6 Reference

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- [3] Hofmann-Wellenhof, B., H. Lichtenegger and J. Collins, 2001: GPS, Theory and Practice. Springer Verlag, (Fifth, revised edition).
- [4] Leick, A., 1995: GPS satellite surveying. John Wiley and Sons.