

SX Series GPS-Aided Inertial Navigation System (INS/GPS) Technical User Guide

LMRK005 INS/GPS

LMRK60 INS/GPS

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1 TABLE OF CONTENTS

1	TAB	LE OF CONTENTS	2
2	ТАВ	LE OF FIGURES	4
3	SAF	ETY AND HANDLING INFORMATION	5
4	GET	TING STARTED	6
	4.1	RS-422/485 TO USB POWER SUPPLY AND CONVERTER CABLE	7
	4.2	HARDWARE APPLICATION NOTE	7
	4.3	GLAMR INSTALLATION	8
	4.3.	1 Introduction	8
	4.4	SELECT APPLICABLE BAUD RATE	5
	4.5	Program Mode & Run Mode1	7
	4.6	SELF-TEST IN GLAMR	8
	4.7	Setting the Data Rate	9
	4.8	SELECT APPLICABLE STOP BITS	0
	4.9	SENSOR DISPLAY OPTIONS	1
	4.9.	1 Gyroscope Unit Selection	1
	4.9.	2 Accelerometer Unit Selection	2
	4.10	PROGRAMMING COEFFICIENTS	3
	4.10	0.1 AHRS Parameters	4 7
	4.10	0.2 GPS Parameters	5 C
	4.10 // 11	DATA PECODD EFATURE	כ ד
	4.11 1/12		γ α
	4.12	SETTING LID INS/GPS FOR EVALUATION	n
	4.14	ALIGNMENT INITIALIZATION OF THE INS/GPS.	1
	4.15	BTK-ENABLED DEVICES	2
	4.16	TROUBLE-SHOOTING COMMON SETUP ERRORS	4
5	ΡΑΤ	ENT AND TRADEMARK INFORMATION	5
6	APP	LICABLE EXPORT CONTROLS	5
7	USE	R LICENSE	5
8	STA	NDARD LIMITED WARRANTY	5
9	ou	ALITY MANAGEMENT SYSTEM	5
10) THE	ORY OF OPERATION 3	6
			~
11	Lan	awiark INS/GPS PRODUCT DESCRIPTION	5
	11.1	OUTLINE AND 3D SOLID MODELS	8
	11.2	CENTER OF GRAVITY	8
	11.3	SENSOR BANDWIDTH	9
	11.4	INS/GPS BLOCK DIAGRAM	J



12 INS/	GPS MESSAGE PROTOCOL	41					
12.1	SERIAL COMMUNICATION SETTINGS	41					
12.2	INS/GPS Message Packet Format	41					
12.3	Sample Data Format	42					
12.3	.1 Interfacing without Glamr						
13 Mou	Inting	44					
14 Ope	ration and Troubleshooting	45					
14.1 14.2	TECHNICAL ASSISTANCE AUTHORIZED DISTRIBUTORS AND TECHNICAL SALES REPRESENTATIVES	45 45					
Revision I	evision History						



2 TABLE OF FIGURES

Figure 1 Example SDK box with SDK to PC USB cabling, GPS antenna, and CD-ROM	16
Figure 2 Typical INS/GPS connectors include: 9-pin (L) or 15-pin (R) Glenair connec	tor7
Figure 3 SDK Installation CD-ROM	8
Figure 4 Glamr setup location on SDK CD-ROM	9
Figure 5 Glamr prerequisite installations	9
Figure 6 Glamr shortcut locations	
Figure 7 Glamr screen before selecting correct COM port settings	
Figure 8 Confirmed correct LINX port with message "success."	
Figure 9 Device Manager LINX-SDM-USB-QS-S port Properties	
Figure 10 Advanced Settings for COM port Latency Timer	
Figure 11 Baud Rate menu	
Figure 12 INS/GPS data in Run Mode at 100 Hz data rate (unit stationary)	
Figure 13 Self-Test, Power, and Run/Program	
Figure 14 Self-Test display when activated	
Figure 15 Mode selection/data rate in "PROGRAM" mode	
Figure 16 Stop bit selection in "PROGRAM" mode	
Figure 17 Gyroscope units of measure selection options	
Figure 18 Accelerometer units of measure selection options	
Figure 19 Accessing the coefficient dialog in "PROGRAM" mode	
Figure 20 AHRS coefficient parameters	
Figure 21 GPS coefficient parameters	
Figure 22 INS coefficient parameters	
Figure 23 Data Recording button	
Figure 24 Saving recorded data files	
Figure 25 Message options for troubleshooting (View menu)	
Figure 26 INS Alignment initialization output with AHRS attitude demo display	
Figure 27 Differential RTK inputs on SDK box	
Figure 28 INS Alignment error demo	
Figure 29 Typical gyroscope bandwidth (250 Hz) of LMRK005 INS/GPS	
Figure 30 Typical accelerometer bandwidth (1100 Hz) LMRK005 INS/GPS	
SX-Series INS/GPS User's Guide Page 4 Copyright © 2019 Gladiator Technologies	Rev. 06/26/2019



Figure 31 INS/GPS block diagram	40
Figure 32 Serial communication settings values	41
Figure 33 Sample INS/GPS data	42

3 SAFETY AND HANDLING INFORMATION

- Always use caution when using the Gladiator ISN/GPS!
- Please refer to your specific product datasheet to determine which appropriate input voltage to use.
- INS/GPS devices/units are sensitive scientific instruments containing shock and vibration sensitive sensors. Excessive shock and/or vibration can damage these sensors and can adversely affect sensor performance and unit output.
- Avoid exposure to electrostatic discharge (ESD). Observe proper grounding whenever handling the INS/GPS.
- Properly attach the connector and ensure that it has been wired correctly before applying power to the INS/GPS.
- Units are shipped from factory in the following default settings, unless otherwise required for customer application:
 - \circ 100 Hz FULL Mode
 - o 921,000 Baud Rate
 - o 1 Stop Bit



4 GETTING STARTED

This section contains directions and references for a quick start to using the INS/GPS.

For additional support, please contact the distributor representing your location. If there isn't a local representative for your location, please contact our Headquarters for assistance and someone from our Sales Team will assist you.

The INS/GPS Software Development Kit (SDK) is an optional product to assist first time users of a Gladiator INS/GPS. This kit provides the user everything they need to facilitate a rapid setup and test of the unit. The SDK includes display software with user-defined options including the following components and is seen in Figure 1:

- Turn-Key Solution for INS/GPS on User PC (all cabling/connectors/software included)
- Easy Integration of Direct INS/GPS RS-422/485 to PC USB Port (example hardware)
- Includes PC Display Software for INS/GPS
- Data Recording Capability
- Multiple User-Selected Field Options for Programming and Initializing the Unit
- Self-Test Button
- Power, Program/Run mode switches
- Antenna



Figure 1 Example SDK box with SDK to PC USB cabling, GPS antenna, and CD-ROM

If multiple units are purchased, the respective test data for each unit is placed on this CD for reference.



4.1 RS-422/485 to USB Power Supply and Converter Cable

Contained in the Software Development Kit is a complete RS-422/485 to USB Converter cable, including power supply and Self-Test button (Figure 2). The power supply uses USB power.

An RS-422/485 to USB converter (requires additional drivers that are included in a CD-ROM) is also included.

The SDK enables the user to quickly connect the INS/GPS to their PC to ease integration and testing. Connect the RS485 (9 or 15-pin) cable to the unit and the USB cable to the PC. The user should not turn on the power switch until all the software is installed.



Figure 2 Typical INS/GPS connectors include: 9-pin (L) or 15-pin (R) Glenair connector

4.2 Hardware Application Note

Please note that any unused RS-485 lines should be terminated by a 3 k Ω resistor with a shielded cable.



4.3 Glamr Installation

4.3.1 Introduction

The LINX SDM-USB-QS-S module requires that device drivers be installed on the host PC before they can interact. The drivers tell the PC how to talk to the module. These drivers are for Windows 7, 8, and 10. The set for Windows are the direct drivers, which offer program functions that allow a custom application to directly control the module through the USB port.



Figure 3 SDK Installation CD-ROM



To install the Glamr SDK application, run the Glamr setup executable found on the CD-ROM sent with your INS/GPS (*Figure 4*).

Name	Date modified	Туре	Size
liamr_Setup_3p2p72p15.exe	11/13/2018 11:50	Application	38,527 KB
LandMark005_INSGPS_USERGUIDE_2018	11/13/2018 11:59	Adobe Acrobat D	0 KB

Figure 4 Glamr setup location on SDK CD-ROM

Status	Requirement
Pending	Microsoft Visual C++ 2017 Redist_x86
Pending	LINX QS Driver Package

Figure 5 Glamr prerequisite installations



ATTENTION: Do **NOT** use the FTDI device driver that Windows 10 provides. It does not work with the LINX product even though they are using the FTDI parts. The PID was changed so it is unique.

Installing Glamr will place a shortcut to the application on the desktop and in the Start Menu.



Figure 6 Glamr shortcut locations

The default Glamr installation directory is:

C:\Program Files (x86)\Gladiator Technologies

In addition to these shortcuts, the installation will also place a Glamr.ini file into:

C:\Users\"username"\AppData\Roaming\Gladiator Technologies\

NOTE: Plug the connector cable into the USB port before you turn the device power on to avoid Windows loading as a mouse driver.



With Glamr successfully installed, open the program and a window will appear as in Figure 7.

🕭 Glad	liator D	isplay 3	.2.72.15	5 Copyright (C) 2007-2018	Gladiator T	echnologies, Inc.	_	Х
Mode	Load	Units	View	Com Port	Baud Rate	Stop Bits	CAN bus		
Output I binar Start R	Resolut y record ecordin	ion: bit Jing g	5	Inertial mo	de: Unknown		SN		
Clei	ar								
IMU seri	ial port (L	.INX SDM-	USB, 921	.600, 8E1) ERRO)R opening				^
									 ~

Figure 7 Glamr screen before selecting correct COM port settings.

The bottom of the Gladiator INS/GPS Display may read "IMU serial port (LINX SDM-USB, 115200, 8E1) ERROR opening." The installer defaults the baud rate to 921600 Mbps, so check the Baud Rate menu to ensure this is the case.

Only one copy of Glamr can be open at a given time. Always make sure there is not another copy open on the task bar. If there are multiple copies of Glamr open, a COM port error will appear when the user tries to interact with the unit.



Now reconnect the USB plug to the SDK. The "LINX" port should have a checkmark next to it. The bottom of the window should now read "IMU serial port (LINX SDM-USB, 115200, 8E1) success." If Glamr is open and no unit is detected, Glamr will attempt to find it by cycling through different baud rates.

🛞 Gla	adiator [Display 3	.2.72.15	і Сору	right (C) 2007-2018	Gladiator T	Technologies, Inc. — 🗌	×
Mode	Load	Units	View	Com	n Port	Baud Rate	Stop Bits	CAN bus	
Outpu	t Resolut	tion: bit	s	~	LINX	ł		SN	
bina	ary recor	ding			COM	1			
Start	Recordin	ng			сом	3			
ſ	nsgs per	sec							
d	ear								
L									
									~

Figure 8 Confirmed correct LINX port with message "success."



Next, open the Windows Device Manager and expand the *Ports (COM & LPT)* section. Right-click on the device labeled "LINX SDM-USB-QS-S" and select "Properties." Open the "Port Settings" tab and then click the "Advanced" button.



Figure 9 Device Manager LINX-SDM-USB-QS-S port Properties



Now change the Latency Timer drop-down setting to 1 msec (from the default 16 msec). Select OK and apply all changes. This setting is necessary for the Windows PC to receive INS/GPS message data at higher message rates without errors.

Advanced Settings for COM4				?	×
COM Port Number: CO USB Transfer Sizes Select lower settings to correct p Select higher settings for faster p Receive (Bytes): Transmit (Bytes):	M4 erformance problems a performance. 4096 ~ 4096 ~	vit low bau	ud rates.	OK Cance Defaul	el Its
BM Options			Miscellaneous Options		
Select lower settings to correct re	esponse problems.		Serial Enumerator		
Latency Timer (msec):	1 ~		Serial Printer		
	1 ^		Cancel If Power Off		
Timeouts	3		Event On Surprise Removal		
Minimum Read Timeout (msec):	5		Set RTS On Close		
Minimum Write Timeout (msec):	7 8 9 10		Disable Modem Ctrl At Startup		

Figure 10 Advanced Settings for COM port Latency Timer

Turn on the power switch on the unit power supply and you should see data appear in the window as shown in Figure 12. You should be able to move the INS/GPS with your hand and see changes in rate, acceleration, and Euler angles for each axis located on-screen. To see rapid change, the record function will capture real-time data without the filter effect of the Glamr display.



4.4 Select Applicable Baud Rate

The baud rate needs to be at least 20% higher than the message rate times the number of bits per message so that INS/GPS may receive commands from the PC. Note that the serial port is half-duplex, so communication between device and host can only go one way. Here is a guide of the relationship between baud rates and message rates:

			Baud Rate Setting $ ightarrow$		
Message		RS-485 Bits/s	115200	921600	
Data Rate	100 Hz	19800	Yes	Yes	
\downarrow	200 Hz	39600	Yes	Yes	
	600 Hz	118800	No	Yes	

Note that 600 Hz Data Mode requires 921600 baud. By default, units are set to 921600 baud and Glamr defaults to communicating at 921600 baud.

After power cycling the INS/GPS, the unit will resume normal functionality.

	Baud Rate Stop Bits						
5	~	115,20	115,200				
		921,60	0	ľ			

Figure 11 Baud Rate menu



ladiator Display 3.2.72.15	🕭 Gladiator Display 3.2.72.15 Copyright (C) 2007-2018 Gladiator Technologies, Inc 🛛 🗙								
Mode Load Units View	Com Port	Baud Rate Stop Bits	CAN bus						
Output Resolution: 16 bits	Inertial mod	le: INSGPS (GPS Sync)		INSGPS	0.5mg () GyroRar	15 g) 1ge: 490			
binary recording	GPS_SYNC		Kalman: 24.12.72.5		Filter Bandwidth: max Board Rev: NG Serial Number: Sat Nov 10 16:00:00 2018				
	InsRoll	1.1147 deg	AccelX	-0.00445 g's	Lat	-0.00003620			
	InsPitch	-2.2930 deg	AccelY	0.00832 g's	Lon	-0.00006010			
	InsYaw	59.500 deg	AccelZ	-0.99746 g's	GPS Hdg	0.00000 deg			
100 msgs per sec	Vnorth	0.00000 m/s	GyroX	0.06164 deg/s	GPS Alt	-188.00 m			
	Veast	-0.00000 m/s	GyroY	-0.04594 deg/s	GPS Vel	0.00000 m/s			
	Vup	0.00000 m/s	GyroZ	-0.01125 deg/s	WeekMs	0 ms			
			Altitude	-188.00 m	VDOP	99.990			
Clear			InsAirSpd	12.532 m/s	hDOP	99.990			
			InsCrab	0.00000	Num SVs	0			
	Pressure	99.693 kPa	TempX	24.964 C					

Figure 12 INS/GPS data in Run Mode at 100 Hz data rate (unit stationary)

The message "Msg out-of-sequence: exp XX, act YY" indicates that the program saw a skip in the message count, where XX and YY can be any integer value. This case can happen at start-up and can be ignored.



4.5 Program Mode & Run Mode

The SDK converter box provides a switch to select either "RUN" mode, or "PROGRAM" mode (Figure 13). These modes indicate which RS-485 serial pair you are communicating with (see datasheet for pinout details).

In RUN mode, the host is expected to only be receiving data from the INS/GPS.

In PROGRAM mode, the host can both send and receive data to/from the INS/GPS. This mode should be used to change communication parameters, as well as for loading/changing coefficient parameters.



4.6 Self-Test in Glamr

Glamr includes a self-test function. The user can initiate the Self-Test by the button (Figure 13), found on the switch box that is included in the INS/GPS SDK.

Press the button to activate a self-test of the sensors. The Glamr display will now show "Self-Test" is activated while also showing the data outputs. This message is located just above the data rate status bar. User should see a delta change in the X, Y, and Z sensor outputs per the data sheet (Figure 14) when Self-Test is initiated.

Note: If the simulated GPS 'outage' time is specified as '-1' then the self-test button will function as a cutout for the GPS signal when pressed, and will no longer affect the sensor outputs.

Refer to the INS/GPS datasheet to see typical activated sensor values.



Figure 13 Self-Test, Power, and Run/Program

Mode Load Units View	Com Port	Baud Rate	Stop Bits	CAN bus			
Output Resolution: 16 bits	Inertial mode: INSGPS (GPS Sync)				INSGPS Version: 24.2.72.4 A	0.5mg (: GyroRan Filter Pa	15 g) nge: 490 ndwidth: max
binary recording	GPS_SYNC				Kalman: 24.12.72.5	Board Re Serial Nu Tue Nov	ev: NG imber: 13 10:06:32 2018
	InsRoll	5.9054 deg	3	AccelX	-0.00653 g's	Lat	47.52846909
** Self Test **	InsPitch	5.8513 deg	9	AccelY	0.00187 g's	Lon	-121.86807251
	InsYaw	64.711 deg	3	AccelZ	-1.0172 g's	GPS Hdg	0.00000 deg
100 msgs per sec	Vnorth	0.05445 m	/s	GyroX	0.98859 deg/s	GPS Alt	257.00 m
	Veast	0.11398 m	/s	GyroY	2.5028 deg/s	GPS Vel	0.22000 m/s
	Vup	0.01469 m	/s	GyroZ	0.84668 deg/s	WeekMs	237992160 ms
				Altitude	-191.00 m	VDOP	1.6300
Clear				InsAirSpd	51.611 m/s	hDOP	1.1100
B				InsCrab	0.00000	Num SVs	7
	Pressure	99.715 kPa		TempX	26.505 C		

Figure 14 Self-Test display when activated



4.7 Setting the Data Rate

The SDK must be set to "PROGRAM" mode to enable changing this field. Glamr enables the user to quickly adjust the data rate. This feature is found in the Mode menu as shown in Figure 15. Raising or lowering the data rate determines how frequently data is sent from the unit to the host. Lower rates will benefit from additional sample averaging.



Figure 15 Mode selection/data rate in "PROGRAM" mode



4.8 Select Applicable Stop Bits

The SDK must be set to "PROGRAM" mode to enable changing this field. When using the INS/GPS, the number of stop bits is one or two as selected by the user. This can be chosen in the Stop Bits drop-down menu and selecting either 1 or 2 per Figure 16. The SX series default is a single Stop Bit.



Figure 16 Stop bit selection in "PROGRAM" mode



4.9 Sensor Display Options

The SDK software can also set the dimensional units of the display. This is selected under Units, as seen in Figure 17-Figure 18.

Note: This is only a cosmetic feature. The dimensional units from the device cannot change.

4.9.1 Gyroscope Unit Selection

🛞 Gladiator Displa	y 3.2.72.15	Copyright (C	C) 2007-2018 Gladiator T	echnologies,	lnc.			×
Mode Load Unit	ts View	Com Port	Baud Rate Stop Bits	CAN bus				
0.	Rate	> 🗸	degrees/sec		INSGPS	0.5mg (1 GyroBan	15 g) Ige: 490	
binary recor	Accel	>	radians/sec		Version: 24.2.72.4 A Kalman: 24.12.72.5	Filter Bar	ndwidth: max	
Start Recordin	Angle	> VC		_		Serial Nu	mber:	
	Velocity	>				Tue Nov	13 10:11:11 2018	
	Altitude	>	2.2600 deg	AccelX	-0.00439 g's	Lat	47.52823257	
		InsPitch	-4.0700 deg	AccelY	0.00840 g's	Lon	-121.86811066	
		InsYaw	142.17 deg	AccelZ	-0.99775 g's	GPS Hdg	310.60 deg	
100 msgs per sec		Voorth	-0.29930 m/s	GyroX	0.06422.dea/s	GPS Alt	226.00 m	
		Veeeb	0.22105 -= /=	Currely		CDC V-I	0.54000 /-	
		veast	0.23195 m/s	Gyror	-0.07571 deg/s	GPS Vei	0.54000 m/s	
		Vup	-0.02711 m/s	GyroZ	-0.01348 deg/s	WeekMs	238271008 ms	
				Altitude	-206.00 m	VDOP	1.6800	
Clear				InsAirSpd	44.982 m/s	hDOP	1.1300	
h				InsCrab	-34.607	Num SVs	7	
		Pressure	99.728 kPa	TempX	27.642 C			

Figure 17 Gyroscope units of measure selection options



4.9.2 Accelerometer Unit Selection

ladiator Displa	y 3.2.72.15	Copyright (C	c) 2007-2018 Gladiato	r Technologies,	lnc.		_	Х
Mode Load Unit	ts View	Com Port	Baud Rate Stop Bit	s CAN bus				
Output Resout	Rate	> hod	e: INSGPS (GPS Svnc)		INSGPS	0.5mg (1 GyroBan	l5g) Ige: 490	
bir	Accel	> 🗸	g's		Version: 24.2.72.4 Kalman: 24.12.72.5	A Filter Bar Board Bo	ndwidth: max	
Start Recordin	Angle	>	meters/sec^2			Serial Nu	mber:	
	Velocity	>	feet/sec^2			Tue Nov	13 10:12:42 2018	
	Altitude	>	2.0496 aeg	AccelX	-0.00439 g's	Lat	47.52849197	
		InsPitch	-4.1741 deg	AccelY	0.00826 g's	Lon	-121.86827850	
		InsYaw	121.18 deg	AccelZ	-0.99776 g's	GPS Hdg	310.60 deg	
100 msgs per sec		Vnorth	-0.08703 m/s	GyroX	0.06574 deg/s	GPS Alt	229.00 m	
		Veast	0.14172 m/s	GyroY	-0.06938 deg/s	GPS Vel	0.15000 m/s	
		Vup	-0.01219 m/s	GyroZ	-0.01219 deg/s	WeekMs	238362512 ms	
				Altitude	-206.00 m	VDOP	1.6900	
Clear				InsAirSpd	75.435 m/s	hDOP	1.1300	
5				InsCrab	-55.926	Num SVs	7	
		Pressure	99.694 kPa	TempX	27.912 C			

Figure 18 Accelerometer units of measure selection options



4.10 Programming Coefficients

The SDK must be set to "PROGRAM" mode to enable changing this field. The SDK software provides users with a display of certain coefficients stored in flash. These coefficients are used internally to modify various aspects of the INS/GPS performance. Modifying these parameters can have a dramatic impact on the output of the device.

A password will be required to access some of these parameters.

Please consult Gladiator Support before changing the locked parameters.

Please refer to the Software Reference Manual for more detail about the individual parameters.

🕭 Gla	🍥 Gladiator AHRS Display 3.2.72.14 Copyright (C) 2007-2018 Gladiator Technologies, Inc 🗌 🗙								\times			
Mode	Load	Units	View	Com Port	Baud Rate	Stop Bits	CAN bus					
Outpur		Load Cal Save Cal Restore F	Params Params actory (s (from file) (to file) Cal Parms				INSGPS Version: 24.2.72.5 A	0.5mg (15 g) GyroRange: Filter Bandwi Board Rev: M Serial Numbe) 490 idth: max NG er:		
		Load AH Save AHI	RS Coef RS Coef:	is (from file) s (to file)			AccelX	-0.01099 g's				
		Show AH	IRS Coe	fs (on displa	y)		lccelY	0.00647 g's				
		Restore F	actory /	AHRS Coefs			AccelZ	-1.0125 g's				
100 n		Load IMI Load Kal	J/AHRS man Pro	Program ogram (fro	(from file) m file)		GyroX GyroY	-0.04980 deg/s 0.00914 deg/s				
		Set Filter				>	-,					
		Zero Out	Airspee	ed			Gyroz	-0.00480 deg/s				
	_	Set Altitu	ıde				MagX	102.23 milli-gauss				
							MagY	-139.53 milli-gauss				
Cle	ar			AirSpd	0.00062 m	n/s	MagZ	480.20 milli-gauss				
				Temp	24.538 C		-	-				
				Pressure	99.712 kP	a	TempX	27.610 C				
												^
												\vee

Figure 19 Accessing the coefficient dialog in "PROGRAM" mode



4.10.1AHRS Parameters

RS Parameters GPS Parameters INS F	Parameters		
Constanting the K		Diada A and Theorie I.d.	
Sensor bandpass Hiter K	1.000000	Pitch Accel Infeshold	0.020 (g)
Blend Filter K	0.025000	Pitch Accel LPF K	0.270
Pitch Angle Delay	1.000000 (s)	Pitch Accel Max g's	2.000 (g)
Accel Filter N	4.000000		
Mag Deviation correction	0.000000 (Deg)	INS Mode Selection	Air Mode $$
Airspeed Offset	10.72 (m/s)		
	10.72		
Operation Mode	OPMODE_FULL 100		
Vehicle offset correction X	0.000 (m)		
Vehicle offset correction Y	0.000 (m)		
Vehicle offset correction 7	0.000 (m)		
	0.000		
Barometric altitude offset	18.30 (m)		
Runtime minimum temperature	17.0 (°C)		
Runtime maximum temperature	147.0 (°C)		
Runtime clock	25 0000 (Hr)		
	20.0000		
		_	

Figure 20 AHRS coefficient parameters

The most common AHRS parameters to change for proper operation are the *vehicle offset correction* values, and *barometric altitude offset*.



4.10.2GPS Parameters

Upload INS/GPS Coefficients		×
AHRS Parameters GPS Parameters INS Parame	eters	
GPS update rate	10.00 (Hz)	
Minimum Satellites Vehicles	4 (Satellites)	
Unit-To-Vehicle mounting transform matrix		
	~	
	X Y Z	
	X 1.00 , 0.00 , 0.00	
	Y 0.00 , 1.00 , 0.00	
	z 0.00 , 0.00 , 1.00	
Unit to GPS Antenna Moment	0.000000 (m)	
·····		
Z	0.250000 (m)	
Minimum velocity before valid heading	1.500000 (m/s)	
Minimum forward velocity for GPS	0.010000 (m/s)	
Time for GPS Start-Up	30.00 (s)	
Default GPS Latitude	47.52870941 (Deg)	
Default GPS Longitude	-121.86820984 (Deg)	
Default GPS Altitude	258.00 (m)	
Default GPS Heading	270.00 (Deg)	
Unlock Password:	LOAD Cance	

Figure 21 GPS coefficient parameters

The most common GPS parameters to change for proper operation the *unit to GPS antenna moment* values, and the *default GPS* values.



4.10.3INS Parameters

Upload INS/GPS Coefficients				×
				~
AHRS Parameters GPS Parameters INS Param	neters			
TAIC Alignment time	Line of	1		
INS Alignment une	150.0	(s)		
GPS input to inertial sensor time delay	0.1670	(s)		
Accel Minimum G	0.0000	(g)		
Gyro saturation delay time	1.00	(s)		
Gyro saturation recovery threshold	10.00	(deg/s)		
Accel saturation delay time	1.00	(s)		
Accel saturation recovery threshold	0.25	(g)		
Gyro Cage			Accel Cage	
∑ x			✓ X	
✓ Y			Y	
∠ Z			Z	
Y (Pitch Only)			Align	
✓ Align			✓ Navigate	
Navigate				
Unlock Password:	LOA	ND		Cancel

Figure 22 INS coefficient parameters

The INS parameters should not need modification for proper operation. Especially without consulting Gladiator Technologies Support.



4.11 Data Record Feature

The SDK software also has a data record feature that captures data outputting from the INS/GPS and puts it into .csv format. This enables the user to easily convert these data files to Excel or database format. The user should click the Start Recording button (Figure 23) to initiate the data record function.

Mada Land Unite View	Com Dort	David Data	Chan Dite	CAN hus	inc.		
Output Resolution: 16 bits	de: INSGPS (GP	Stop Bits S Sync)		INSGPS Version: 24.2.72.4 A	0.5mg (i GyroRan	15 g) nge: 490	
binary recording Start Recording	GPS_SYNC				Kalman: 24.12.72.5	Board Re Serial Nu Tue Nov	ev: NG Imber: 13 10:14:23 2018
	InsRoll	1.8024 deg		AccelX	-0.00457 g's	Lat	47.52855682
	InsPitch	-4.4060 deg	,	AccelY	0.00835 g's	Lon	-121.86811066
	InsYaw	104.59 deg		AccelZ	-0.99781 g's	GPS Hdg	310.60 deg
100 msgs per sec	Vnorth	-0.02211 m	/s	GyroX	0.06246 deg/s	GPS Alt	246.00 m
	Veast	0.08961 m/	S	GyroY	-0.07301 deg/s	GPS Vel	0.04000 m/s
	Vup	-0.00656 m	/s	GyroZ	-0.01066 deg/s	WeekMs	238463328 ms
				Altitude	-189.00 m	VDOP	1.6000
Clear				InsAirSpd	110.06 m/s	hDOP	1.0500
<u> </u>				InsCrab	-72.605	Num SVs	8
	Pressure	99.672 kPa		TempX	28.141 C		

Figure 23 Data Recording button

After selecting "Start Recording," Glamr will prompt the user to designate a filename and location before the beginning the recording. Note that writing to pre-existing filename will **not** append the data and instead overwrite it with the new recording. At this prompt, click Open as shown in Figure 24. After the filename and location are selected, click the desired length of time to record then click OK.



Select recording file										×
$\leftrightarrow \rightarrow \neg \uparrow \bigtriangleup$ OneDrive					~	ۍ ٢	earch One	Drive		P
Organize • New folder										0
> 🖈 Quick access	^ N	ame	^	Date modified	Type earch.		Se	ce .		
) 🖾 OneDrive				ing name making our s						
🗸 🛄 This PC										
3D Objects										
> 🛄 Desktop										
> 🗄 Documents										
> 🕹 Downloads										
> 👌 Music										
> 📰 Pictures										
> 🚼 Videos										
> 🏪 OS (C:)										
>										
>										
A REPORT OF A	v									_
File name: *.o	3V					Nº 1	comma sej	parated val	lue files (*. ×
							Open		Cancel	

Figure 24 Saving recorded data files

If a recording time was specified by the user, the time remaining will appear below the Start Record button. To stop recording, simply click the "Stop Recording" button.



4.12 Troubleshooting with Messages

If you are experiencing difficulties interfacing the INS/GPS to your system, Glamr can be commanded to display messages to and from the unit in the message window. This is done via the View menu per Figure 25.

ladiator Display 3 🛞	.2.72.15	i Copyright ((C) 2007-2018 Gladiator 1	Fechnologies,	lnc.		_	×
Mode Load Units	View	Com Port	Baud Rate Stop Bits	CAN bus				
Output Resolution: 16 b	[Demo (Norma	al)		INSGPS	0.5mg (1 GyroRan	15 g) Ige: 490	
binary recording	[Demo (High [Dynamic)		Version: 24.2.72.4 A Kalman: 24.12.72.5	Filter Bar Board Re	ndwidth: max	
Start Recording	S	Show TX msg	to AHRS			Serial Nu Tue Nov	mber: 13 10:35:44 2018	
	S	Show RX (dec	oded) msg bytes	ccelX	-0.00178 a's	Lat	47.52848053	
	5	Show RX (raw	insert) msg bytes					
		InsPitch	-2.6234 deg	AccelY	0.00912 g's	Lon	-121.86820221	
		InsYaw	74.534 deg	AccelZ	-0.99803 g's	GPS Hdg	123.98 deg	
101 msgs per sec		Vnorth	0.0 49 06 m/s	GyroX	0.06340 deg/s	GPS Alt	250.00 m	
		Veast	0.17578 m/s	GyroY	-0.07957 deg/s	GPS Vel	0.20000 m/s	
		Vup	-0.00922 m/s	GyroZ	-0.01828 deg/s	WeekMs	239744768 ms	
				Altitude	-216.00 m	VDOP	1.8400	
Clear				InsAirSpd	257.19 m/s	hDOP	1.1000	
Cicur				InsCrab	-109.97	Num SVs	8	
		Pressure	99.746 kPa	TempX	29.466 C			
AHRS (76): 53 57 03 00	0 fb ff fe	e ff fc ff 12 00	34 f8 82 0b 2e 00 5b ff e	8 01 d6 c2 d2 f	f e8 ff 41 1d 03 00			~
0c 00 ff ff 6e 00 fa fe 2 38 ff fa 00 0d 00 6e 30	21 1d 12	d5 75 64 b8 0	0 6e 00 40 45 54 1c 80 6	4 5c b7 89 2d 4	a 0e eb 07			
	00020							
								~

Figure 25 Message options for troubleshooting (View menu)



4.13 Setting Up INS/GPS For Evaluation

Prior to testing the INS/GPS, the user should identify the mounting position and orientation of the unit and the GPS antenna. Take note of the parameters (X, Y, Z) shown below:



Set the unit to PROGRAM mode.

Set the AHRS coefficients to match appropriately (4.10). Mainly the unit to GPS antenna moment values. If the unit is placed away from the vehicle center of rotation, then the vehicle offset correction values should also be set.

Before starting testing, set the default latitude, longitude, altitude, and heading (4.10.2). Set the current altitude with Glamr, or set the barometric altitude offset such that the displayed barometric altitude represents the current altitude.

Switch the unit to RUN mode, and cycle unit power to start the INS/GPS alignment process.



4.14 Alignment Initialization of the INS/GPS

Before powering the unit ON, follow these steps:

- Make sure the unit is on a stable surface and will not be moved during initialization
- Ensure the SDK is switched to "RUN" mode

Open Glamr and power the unit ON. Glamr will display that it is beginning an alignment process. The unit must not be moved during the INS initialization as during this period the INS Coordinate frame is being established. Moving the unit during this two-minute initialization period will result in permanent angle output errors until the user cycles power and re-initializes the unit. You also open the Attitude Indicator on initial application open to observe the stability of the unit during this period by going to "View" > "Demo".

After approximately two-minutes (user-configurable) Glamr will indicate that alignment has completed. In addition, the attitude indicator should be flat and indicate no roll or pitch error if on a flat stable surface.



Figure 26 INS Alignment initialization output with AHRS attitude demo display

Note: The INS/GPS can be externally commanded to restart the alignment initialization process while in PROGRAM mode. More details about this command can be found in the Software Reference Manual.



4.15 RTK-Enabled Devices

Gladiator Technologies' INS systems that have RTK capability enabled can leverage the additional information to provide a more precise GPS solution. RTK input can be supplied to these INS systems via a differential serial input with the following protocol specifications:

- RS-485 Differential input
- 115200 baud, 8 data bits, 1 stop bit, no parity
- RTCM3 format

When a valid RTK signal is detected and an RTK update is delivered to the system, the INS will flag this in the status byte. This can also be observed with Glamr to confirm a valid RTK input.



Figure 27 Differential RTK inputs on SDK box



Gladiator Display 3.2.72.19	ladiator Display 3.2.72.19 Copyright (C) 2007-2019 Gladiator Technologies, Inc 🗌									
Mode Load Units View	Com Port	Baud Rate Stop Bits								
Output Resolution: 16 bits	Inertial mod	de: INSGPS (GPS Sync)		LMRK60 INSGPS	0.5mg (: GyroRar Filter Ba	15 g) 1ge: 490 ndwidth: max				
binary recording	GPS_SYNC,	S_SYNC, RTK Serial Number:								
	InsRoll	-0.04000 deg	AccelX	-0.01102 g's	Lat	47.52854919				
	InsPitch	-0.79852 deg	AccelY	-0.00129 g's	Lon	-121.86850739				
	InsYaw	252.23 deg	AccelZ	-1.0000 g's	GPS Hdg	99.690 deg				
100 msgs per sec	Vnorth	-0.18016 m/s	GyroX	0.00094 deg/s	GPS Alt	228.00 m				
	Veast	-0.58039 m/s	GyroY	0.00258 deg/s	GPS Vel	1.1800 m/s				
	Vup	-1.4288 m/s	GyroZ	-0.00504 deg/s	WeekMs	326230112 ms				
			Altitude	246.00 m	VDOP	1.9300				
Clear			InsAirSpd	1.4793 m/s	hDOP	1.3000				
			InsCrab	-19.900	Num SVs	6				
	Pressure	98.402 kPa	TempX	27.094 C						
IMU serial port (LINX SDM-USB, Accel re-scale set to 0.5	921600, 8E1) success					^			
Gyro re-scale set to 1.5 Pressure sensor detected.										
							~			

Figure 28 Glamr displaying a valid RTK input has been detected.



4.16 Trouble-shooting Common Setup Errors

Do NOT move the unit during INS alignment initialization!

The most common setup error is moving the unit or significantly bumping the unit during INS Alignment Initialization. If the unit is rotated it will corrupt the INS Coordinate Frame and as a result give you a permanent angle error even after INS Navigate has been confirmed.

If a problem is detected during alignment initialization the unit will report an "alignment error" in the status byte. see the Software Reference Manual for more details. Glamr will also display an alignment error message if this is reported in the status byte.





5 PATENT AND TRADEMARK INFORMATION

All Gladiator Technologies SX Series INS/GPS devices are newly developed units containing significant intellectual property and are expected to be protected by United States of America (USA) and other foreign patents pending. LandMarkTM is an official and registered Trademark that identifies Gladiator Technologies brand name for our digital inertial and integrated GPS systems products.

6 APPLICABLE EXPORT CONTROLS

LandMark INS/GPS have been self-classified by Gladiator Technologies with pending Commodity Classification by the U.S. Department of Commerce under the Export Administration Regulations (EAR), as ECCN7A994 and as such may be exported without a license using symbol NLR (No License Required) to destinations other than those identified in <u>country group E of supplement 1 to Part 740</u> (commonly referred to as the T-5 countries) of the Export Administration Regulations. Items otherwise eligible for export under NLR may require a license if the exporter knows or is informed that the items will be used in prohibited chemical, biological, or nuclear weapons or missile activities as defined in Part 774 of the EAR. Copies of official U.S. Department of Commerce Commodity Classifications are available upon request.

7 USER LICENSE

Gladiator Technologies grants purchasers and/or consignees of Gladiator INS/GPS a no-cost, royalty-free license for use of the following software code for use with Gladiator INS/GPS. Companies or persons not meeting the criteria as a purchaser or consignee are strictly prohibited from use of this code. Users in this category wanting to use the code may contact the factory for other user licensing options.

8 STANDARD LIMITED WARRANTY

Gladiator Technologies offers a standard one-year limited warranty with the factory's option to either repair or replace any units found to be defective during the warranty period. Opening the case, mishandling or damaging the unit will void the warranty. Please see Gladiator Technologies' Terms & Conditions of sale regarding specific warranty information.

9 QUALITY MANAGEMENT SYSTEM

Gladiator Technologies' Quality Management System is third party certified to AS9100 Requirements for Aviation, Space and Defense (latest revision). To view our current certificate please go to www.gladiatortechnologies.com or www.lkdaerospace.com.



10 THEORY OF OPERATION

Currently, Gladiator INS/GPS devices support:

- Digital 6 DOF MEMS INS/GPS that outputs x-, y-, and z-axis angular rates, x-, y-, and z-axis linear acceleration data, temperature, x-, y-, and z-axis magnetometer data, barometric pressure, AHRS roll, pitch, and yaw angles, GPS VDOP & HDOP, North/East/vertical velocities, INS roll, pitch, and yaw angles, INS crab angle, INS airspeed, Latitude, Longitude, GPS time, baro altitude, GPS altitude, GPS velocity, GPS heading, and number of satellites vehicles (SV).
- Utilizing Gladiator's proprietary thermal modeling process, these INS/GPS units are fully temperature compensated, with temperature-corrected biases and scale factors, plus corrected misalignment and g-sensitivity.

INS/GPS Features:

- The RS-422/485 serial digital interface provides serial data outputs enabling the user to monitor the outputs during use. Internal sampling is done at 4.8 kHz. Over-sampling is done on the INS/GPS inertial sensors at 2X when set at 100 Hz and then averaged to improve the noise of the MEMS sensors. The nominal output rate in the INS/GPS is 100 Hz ±5%. An RS-422/485 to USB converter is available in Gladiator's INS/GPS Software Development Kit (SDK) to enable a quick INS/GPS to PC integration.
- Three MEMS gyro signals with active filtering and over sampling when set at 100 Hz with a 16-bit A/D converter. Gladiator INS/GPS units are available in the following standard gyroscope ranges:

 ±490°/sec
- Three MEMS accel signals with digital filtering and oversampling when set at 100 Hz with a 16-bit A/D converter. Gladiator INS/GPS units are available in the following standard accelerometer ranges:
 - o 15g
- The internal temperature sensors outputs are over sampled when set at 100 Hz with a 16-bit converter. These temperature measurements are co-located with the x-, y-, and z-axis INS/GPS to enable accurate temperature compensation of the INS/GPS outputs. The x gyro (XGYR) temperature is reported to the user.
- The calibration process measures temperature at a minimum of five set points from -50°C to +85°C and a nine-point correction table is generated that identifies temperature-based offsets for each of the INS/GPS data sets.
- Though a precision orthogonal mounting block is used in testing LandMark[™] INS/GPS units, misalignment error correction is also essential in enabling high performance navigation from a MEMS inertial sensor assembly. The calibration process also corrects and compensates for internal misalignment errors for all sensors in all three axes.



- G-sensitivity errors associated with the INS/GPS devices are also modeled and calibrated to correct these performance errors associated with acceleration inputs in all three INS/GPS axes.
- All calibration data is loaded into an internal memory EEPROM enabling a look-up table for thermal modeling correction of the outputs during use.

LandMark INS/GPS datasheets are available via download on our website. The latest version of all documentation can be found on the Gladiator Technologies website at <u>www.gladiatortechnologies.com</u>. Copies of the User's Guides are available upon request at support@gladiatortechnologies.com.

The LandMark INS/GPS SDK software design enables updates to the INS/GPS interface. As these software enhancements and upgrades become available, Gladiator will make these available to our INS/GPS customers.



11 LandMark INS/GPS PRODUCT DESCRIPTION

Designed for commercial stabilization and aircraft applications, the LandMark INS/GPS is ideal for commercial applications requiring high inertial performance approaching "small RLG or open loop FOG-Class," yet available at a much lower cost. Other key advantages include low power consumption, small size, light weight, and no inherent wear out modes for long life. The signature features of the LandMark INS/GPS are the exceptionally low noise and bias performance.

The unit is environmentally sealed in a rugged enclosure and has a MIL-SPEC connector to withstand environmental vibration and shock typically associated with commercial aircraft requirements. LandMark INS/GPS units are well suited for demanding commercial applications including: rail track telemetry, navigation, flight control, precision imaging, platform and antenna stabilization, flight testing, and laboratory use.

For the exact specifications of your INS/GPS, please refer to the datasheet on the website.

11.1 *Outline and 3D Solid Models*

Please visit the product page of your INS/GPS on the Gladiator website at <u>http://www.gladiatortechnologies.com/gps-aided/</u>. Here you can download the 3D Solid Model, 2D outline drawing, and other product information.

11.2 *Center of Gravity*

Some applications need to know the center of gravity (CG) of the package. Please refer to the mechanical drawing for details.



11.3 Sensor Bandwidth

The bandwidth of a typical Gladiator sensor can be seen in Figures 30-31. The maximum bandwidth of our gyroscopes is 250 Hz (Figure 29) and the maximum bandwidth of our accelerometers is 1100 Hz (product dependent). To verify these values, we collect one minute of data at 2500 Hz, then perform a Fast Fourier Transform and plot the result.



Figure 30 Typical gyroscope bandwidth (250 Hz) of LMRK005 INS/GPS



Figure 31 Typical accelerometer bandwidth (1100 Hz) LMRK005 INS/GPS



11.4 INS/GPS Block Diagram

Gladiator INS/GPS units have internal functionality which can be represented with a block diagram. Figure 31 is a high-level representation of the INS/GPS.



Figure 32 INS/GPS block diagram



12 INS/GPS MESSAGE PROTOCOL

12.1 Serial Communication Settings

INS/GPS units are shipped to the customer in a standard configuration of 921,600 baud (in 100 Hz FULL Mode) and 1 Stop bit.

Parameter	Value
Bits/second:	115200, 921600
Start bits:	1
Data bits:	8
Parity:	E
Stop bits:	1 or 2 (Selectable)

Figure 33 Serial communication settings values

12.2 INS/GPS Message Packet Format

At power-up, the INS/GPS enters operational mode using the last commanded mode setting. **Please refer** to the Gladiator Technologies Software Reference for additional information.



12.3 Sample Data Format

Figure 33 provides a sample INS/GPS data format output in Excel.

MSGCOU	NGYRX (°/s)	GYRY (°/s)	GYRZ (°/s)	ACCX (mg	ACCY (mg	ACCZ (mg	TEMPX (C	MAGX (m	MAGY (m	MAGZ (m	PRESSURE	ROLL (deg	PITCH (de	HEADING	GPS_VDO	GPS_HDO	INS_VNor
45	5 1.53	0.19	1.03	-77.5	72.5	-1027.5	24.21	123	-186	386	102.1	0.63	-0.23	63.42	1.37	0.9	18.9
46	-3.08	1.05	0.04	37	-35	-940	24.21	120	-191	390	102.1	0.61	-0.21	63.4	1.37	0.9	18.91
47	7 2.57	-3.81	0.93	-68.5	75	-1065	24.21	114	-194	392	102.1	0.63	-0.25	63.4	1.37	0.9	18.86
48	3 -2.71	1.1	0.18	37.5	-84	-966	24.21	110	-190	387	102.1	0.6	-0.23	63.39	1.37	0.9	18.91
49	2.22	-1.11	0.75	-65	74.5	-1081	24.21	115	-192	391	102.11	0.61	-0.24	63.38	1.37	0.9	18.89
50	-2.5	1.3	0.49	69.5	-44.5	-947.5	24.21	118	-187	387	102.11	0.59	-0.22	63.37	1.37	0.9	18.92
51	L 0.6	-4.88	0.6	-83	128	-1110	24.21	118	-184	383	102.11	0.58	-0.27	63.35	1.37	0.9	18.86
52	-0.36	3.9	0.3	7	-114	-917	24.21	120	-186	383	102.11	0.57	-0.23	63.34	1.37	0.9	18.95
53	-2.53	-3.45	0.6	-69.5	99.5	-1069.5	24.21	120	-191	383	102.11	0.54	-0.28	63.32	1.37	0.9	18.82
54	1 0.49	2.26	-0.1	33	-105	-931	24.21	115	-190	387	102.12	0.54	-0.25	63.31	1.37	0.9	18.88
55	-0.96	-2.46	0.93	-76.5	90	-1073	24.21	120	-193	389	102.12	0.52	-0.29	63.3	1.37	0.9	18.83
56	-2.61	3.45	0.13	33.5	-42	-916	24.2	121	-191	390	102.12	0.51	-0.25	63.28	1.37	0.9	18.89
57	7 0.24	-4.18	0.45	-41.5	109	-1089	24.2	119	-187	384	102.12	0.51	-0.3	63.27	1.37	0.9	18.81
58	3 1.13	2.52	0.72	1.5	-63.5	-945.5	24.21	124	-191	383	102.12	0.52	-0.26	63.25	1.37	0.9	18.89
59	-3.38	-3.04	0.1	-37	69	-1083	24.21	122	-193	387	102.12	0.48	-0.3	63.24	1.37	0.9	18.83
60	1.51	2.55	0.48	-6	-71.5	-937.5	24.21	118	-193	384	102.12	0.49	-0.26	63.23	1.37	0.9	18.89
61	L -0.6	-4.39	0.25	-57	39.5	-1086.5	24.22	120	-196	390	102.12	0.48	-0.31	63.21	1.37	0.9	18.82
62	-2.84	4.88	0.57	3.5	-25	-947.5	24.22	122	-192	386	102.12	0.47	-0.24	63.2	1.37	0.9	18.92
63	-1.49	-4.41	0.15	9	62	-1078	24.22	124	-190	385	102.12	0.46	-0.28	63.18	1.37	0.9	18.84

INS_VEast	INS_VUp (INS_ROLL	INS_PITCH	INS_HEAD	INS_CRAB	INS_AIRSF	INS_LATIT	INS_LONG	INS_TIME	BARO_AL	GPS_ALTI1	GPS_VELC	GPS_HEAD	GPS_SVS (K_STATUS A	_STATUS
-25.28	-0.35	1.25	-0.64	306.78	93.36	31.63	47.58539	-122.226	5.11E+08	20	20	31.56	306.8	11	0	2
-25.29	-0.35	1.22	-0.63	306.78	93.39	31.86	47.58539	-122.226	5.11E+08	19	20	31.58	306.8	11	0	81
-25.22	-0.37	1.24	-0.67	306.79	93.39	31.7	47.58539	-122.226	5.11E+08	20	20	31.49	306.8	11	0	2
-25.29	-0.36	1.21	-0.66	306.79	93.41	31.87	47.5854	-122.226	5.11E+08	20	20	31.58	306.8	11	0	81
-25.25	-0.37	1.24	-0.67	306.8	93.42	31.66	47.5854	-122.226	5.11E+08	19	20	31.54	306.8	11	0	2
-25.29	-0.36	1.21	-0.66	306.81	93.44	31.88	47.5854	-122.226	5.11E+08	19	20	31.58	306.8	11	0	81
-25.2	-0.39	1.22	-0.7	306.81	93.46	31.73	47.5854	-122.226	5.11E+08	19	20	31.47	306.8	11	0	2
-25.32	-0.37	1.21	-0.66	306.81	93.48	31.83	47.5854	-122.226	5.11E+08	19	20	31.63	306.8	11	0	81
-25.14	-0.38	1.19	-0.7	306.82	93.5	31.64	47.5854	-122.226	5.11E+08	19	20	31.41	306.68	11	1	2
-25.23	-0.37	1.19	-0.68	306.81	93.52	31.84	47.58541	-122.226	5.11E+08	18	20	31.51	306.68	11	0	81
-25.16	-0.38	1.18	-0.7	306.81	93.51	31.61	47.58541	-122.226	5.11E+08	18	20	31.43	306.68	11	0	2
-25.24	-0.37	1.16	-0.67	306.82	93.54	31.83	47.58541	-122.226	5.11E+08	18	20	31.53	306.68	11	0	81
-25.13	-0.39	1.16	-0.71	306.82	93.55	31.65	47.58541	-122.226	5.11E+08	18	20	31.4	306.68	11	0	2
-25.22	-0.38	1.17	-0.68	306.83	93.58	31.85	47.58541	-122.226	5.11E+08	18	20	31.51	306.68	11	0	81
-25.14	-0.39	1.13	-0.71	306.83	93.6	31.63	47.58541	-122.226	5.11E+08	18	20	31.42	306.68	11	0	2
-25.22	-0.38	1.15	-0.69	306.83	93.61	31.84	47.58541	-122.226	5.11E+08	18	20	31.51	306.68	11	0	81
-25.12	-0.4	1.14	-0.73	306.84	93.63	31.66	47.58541	-122.226	5.11E+08	18	20	31.39	306.68	11	0	2
-25.25	-0.38	1.11	-0.68	306.84	93.64	31.8	47.58541	-122.226	5.11E+08	18	20	31.55	306.68	11	0	81
-25.15	-0.4	1.1	-0.73	306.84	93.67	31.67	47.58542	-122.226	5.11E+08	18	20	31.42	306.75	11	1	2

Figure 34 Sample INS/GPS data

Please note that when a customer uses the Glamr interface the program automatically rescales the INS/GPS outputs. This is displayed in Figure 33.



12.3.1 Interfacing without Glamr

If you are not using the Glamr interface be aware that the outputs require a divide by function. Additionally, you should use the LSB's noted per your INS/GPS datasheet. For example, for a 490 °/s rate range INS/GPS the 16-bit LSB is 0.015 °/s:

$$LSB = \frac{(Sensor Range)}{2^{Bit Resolution-1}} = \frac{490 \text{ }^{\circ}/s}{2^{15}} = 0.015 \text{ }^{\circ}/s$$

The calculations for higher bit resolutions are as follows:

$$\frac{490\,^{\circ}/s}{2^{23}} = 0.00006\,^{\circ}/s$$

$$\frac{490\,^{\circ}/s}{2^{31}} = 0.00000023\,^{\circ}/s$$

For a 2000 °/s gyro at 16-bit:

$$\frac{2000\,^{\circ}/s}{2^{15}} = 0.061\,^{\circ}/s$$

For temperature, $0.01 \,^{\circ}$ C should be used. Note that in the exponent, one bit is subtracted from the total bit resolution to account for both positive and negative values (effectively dividing it by two).



13 Mounting

Mounting for the INS/GPS accommodates both metric and U.S. mounting screws. Mount the unit to a flat surface with 4ea M2 metric stainless-steel screws (or 2-56). The minimum torque requirement is 32 in/oz. Be sure that the surface that you are mounting to is as clean and as level as possible to eliminate potential alignment errors. Adequate mounting to a surface should fall within a flatness of +/- 0.001" or +/- 0.025 mm.

Failing to mount the unit in this fashion can result in unaccounted stress in the sensors and therefore may affect data output. Gladiator Technologies strongly encourages the user to mount the unit correctly in the described manner to ensure proper functioning.



14 Operation and Troubleshooting

14.1 Technical Assistance

Please contact the factory or your local Gladiator Technologies sales representative's office for technical assistance.

Technical Support - USA
Gladiator Technologies
Attn: Technical Support
8020 Bracken Place SE
Snoqualmie, WA 98065 USA
Tel: 425-396-0829 x241
Fax: 425-396-1129
Email: support@gladiatortechnologies.com
Web: www.gladiatortechnologies.com

14.2 Authorized Distributors and Technical Sales Representatives

If you need additional assistance, please contact your local distributor and/or the factory for further technical support:

http://www.gladiatortechnologies.com/international-customers/



Revision History

Rev	Date	Description	Page Number(s)
С	6/26/2019	Added section 4.15	33
В	5/9/2019	Added Hardware note Section 4.2	8
А	1/9/2019	Initial document creation	-