

# **GPSFox** Quick Guide for MC Series GNSS ADR/ GNSS ADR+UDR

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## About LOCOSYS

LOCOSYS Technology Inc. established in 1995, a company that provide services the scope of which spans from both hardware and software in Global Navigation Satellite System (GNSS), Wireless Communication, Embedded System to Avionics, Automotive and Consumers electronics. LOCOSYS Technology Came from a well-known research organization of information industry, LOCOSYS sustains a strong R&D in Software, Hardware and system integration. Through its self own (International Automotive Task Force, IATF) IATF16949: 2016 / ISO 9001: 2015 certified production lines in Taiwan and carefully selected sites in China. LOCOSYS is a qualified supplier to tier 1 & tier 2 manufacture in Automotive industry (design house, EMS, OEM, ODM) and be the 2017 best partner of 'Automotive Dead Reckoning' in China automotive industry and provides solutions and services to various market segments. Stay in  $\alpha$ -level qualified module designer and supplier in the international market, deal the partnership with more than 20 Well-known distributors overseas, to provide our customers a complete OEM and ODM services.

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**We will then contact you directly.**

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## **1. Introduction**

This document is the user guide of GPSFox of MC-1612-DX LOCOSYS GPS/GNSS DR (Dead Reckoning) products. Before you start reading the below contents, please recognize if your DR products is for ADR (Automotive Dead Reckoning) or UDR (Untethered Dead Reckoning) application.

## **2. Getting Started**

### **2.1 System Requirements**

To use GPSFox on a Windows PC, you must have at least the following:

- Operating System : Windows XP, Windows 7, or Windows 10
- CPU: Celeron 1.6GHz or above
- System Memory (RAM) : 2048 MB RAM and above
- Hard Disk : 50MB free space
- Screen : 800x600, "16-bit High Color" screen
- Internet: 802.11a/b/g/n/ac or Ethernet

### **2.2 Installation**

Make sure the driver for USB has been successfully installed on your host PC/Notebook, and just copy GPSFox.exe to a new empty folder on your hard disk .Create a shortcut on desktop if necessary.

(The USB driver can be downloaded from our website:

<http://www.locosystech.com> )

### **2.3 Uninstallation**

This program does not add any key to system registry. If you don't want it to keep it no more, just delete the provided files and its shortcut from your hard disk.

### 3. Launch GPSFox

1. Please open GPSFOX software and then choose a corresponding COMPort.

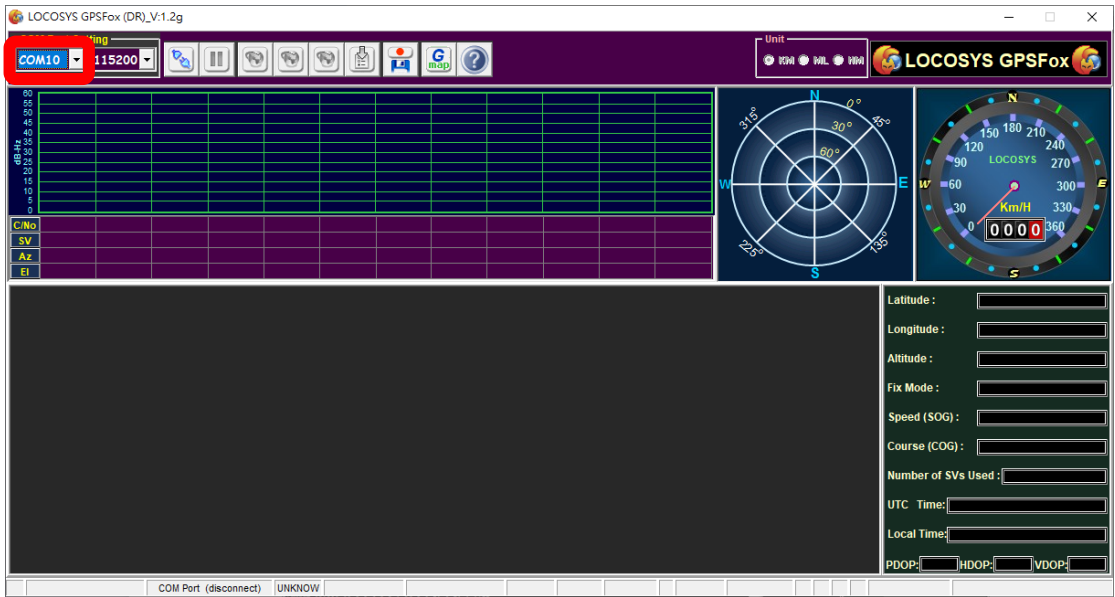


Figure 1: Choose a corresponding

2. Please choose corresponding Baudrate.

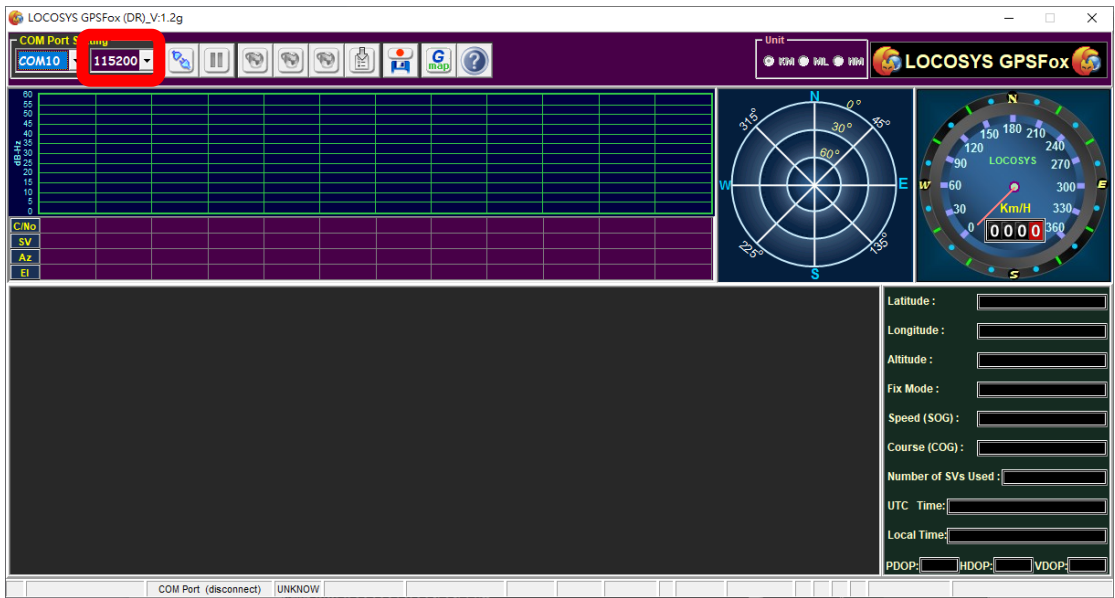


Figure 2: Choose corresponding Baudrate

3. Please press the “Connect to GNSS Receiver” button to connect your GNSS module.

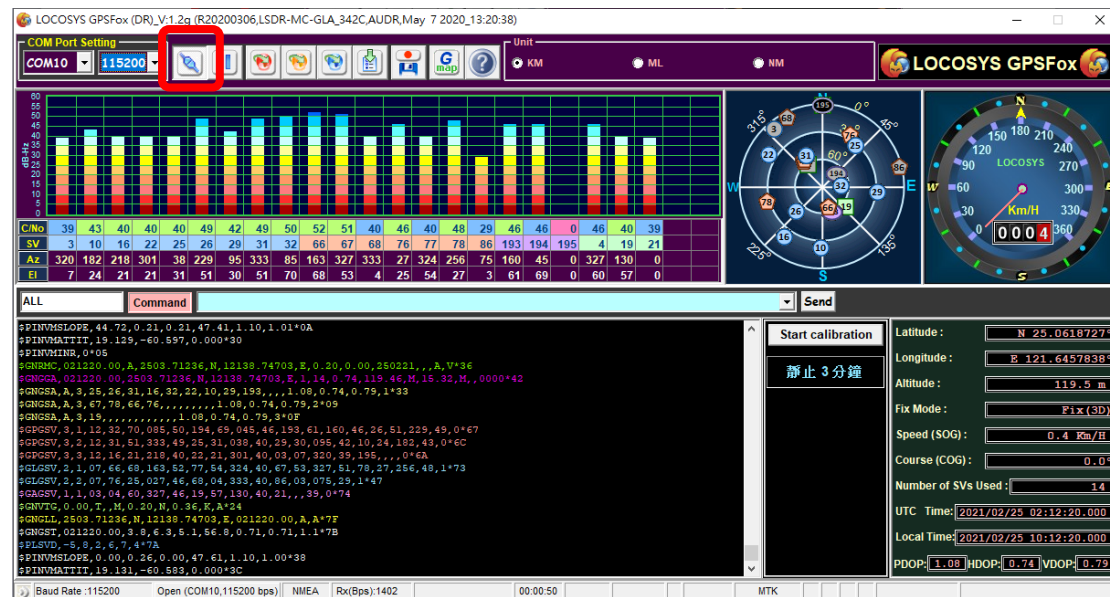


Figure 3: Connect to GNSS Receiver button

4. If you hope to disconnect your connected module, please press “Disconnect” button.

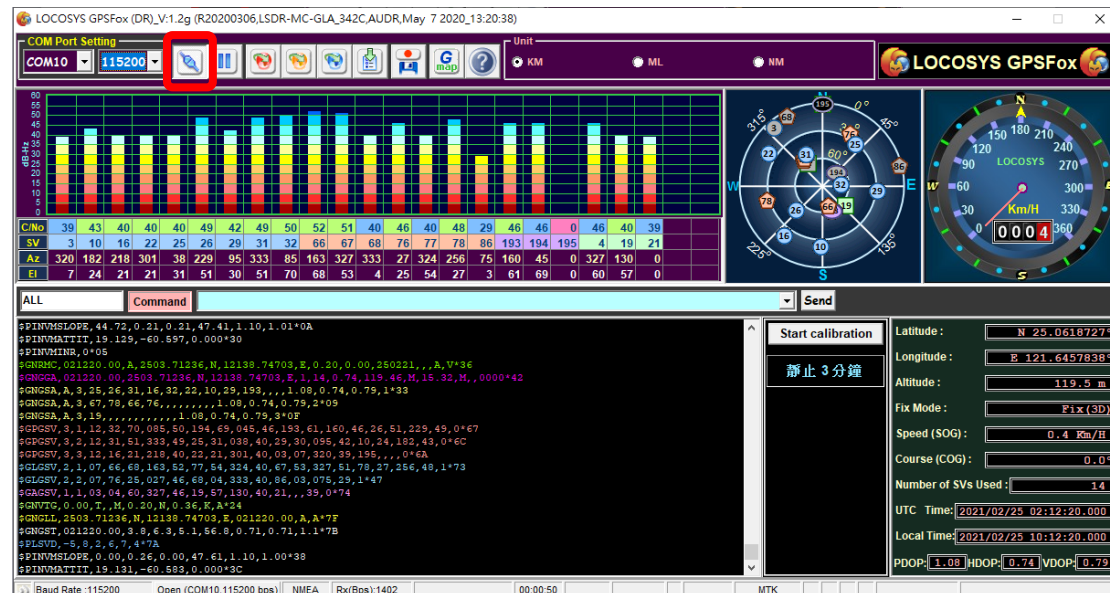


Figure 4: Disconnect button



5. If you want to view NMEA signals, please press “Click to Pause” button to temporarily pause the NMEA signals input, and then you can view its signals.

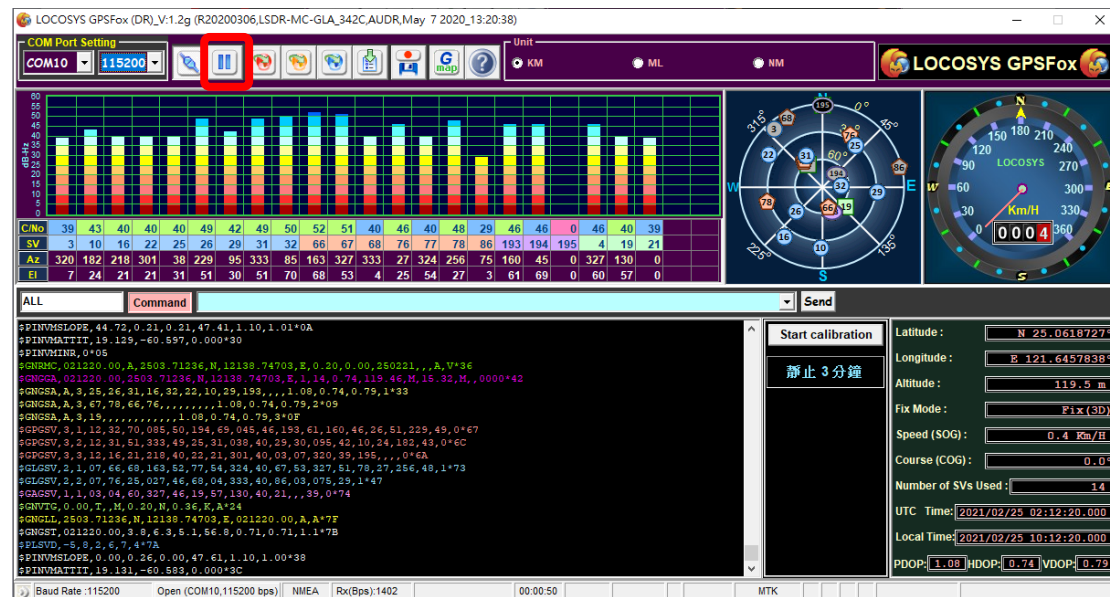


Figure 5: Click to Pause button

6. When you first connect your module, please press “Cold Start” button or “Factory Default” button to clear the original positioning data of the module. Then it can be re-located.

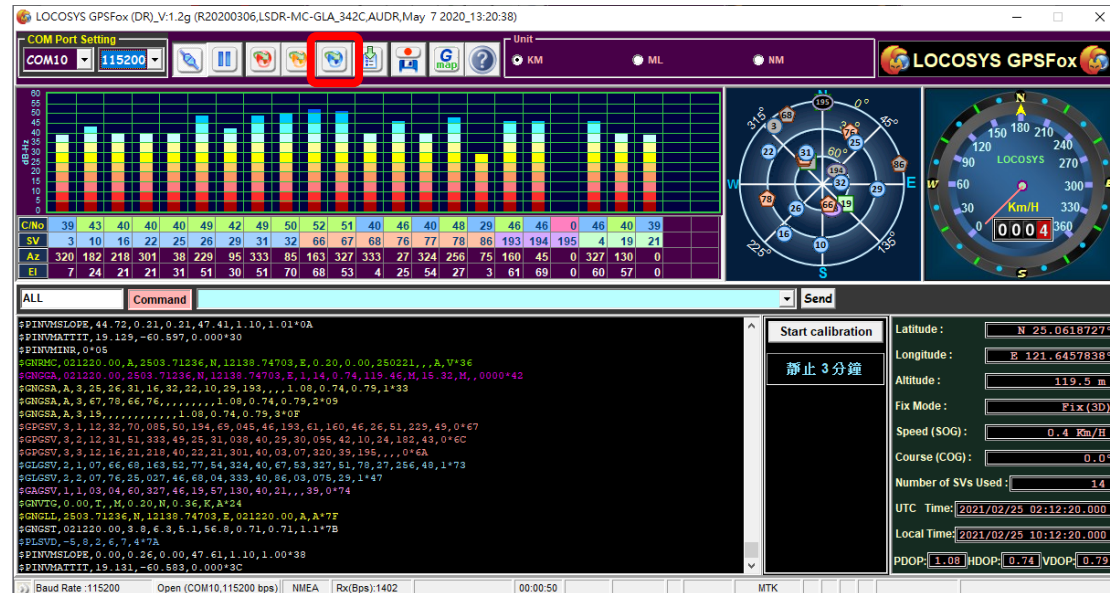


Figure 6-1: Cold Start button

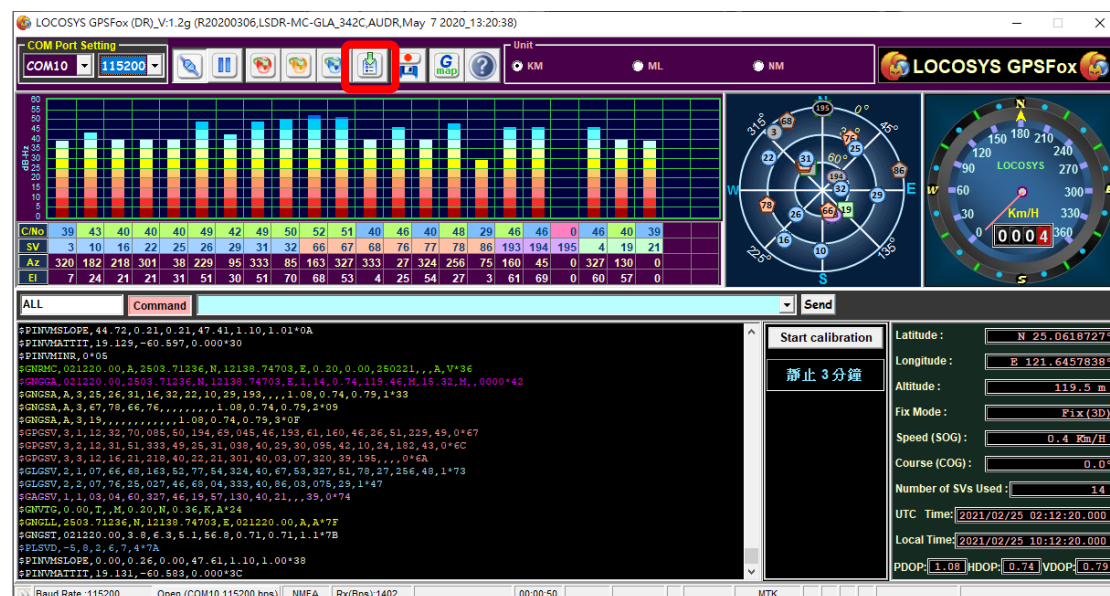


Figure 6-2: Factory Default button

7. Click **Start calibration** to initiate Calibration Mode, shown as below.

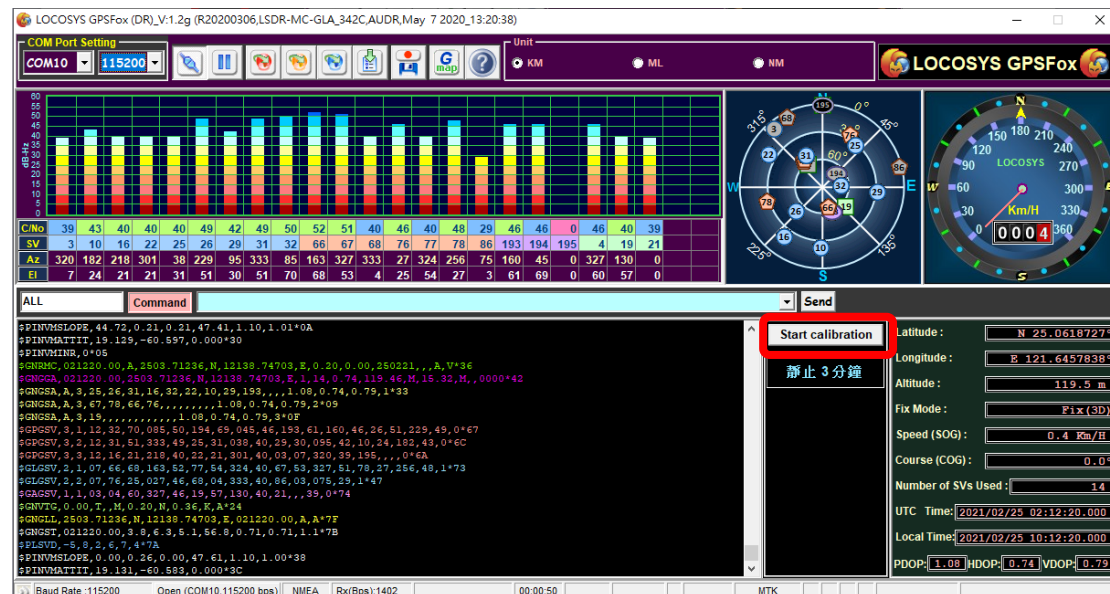


Figure 7: Click to Start Calibration

8. After click Start calibration, you will see a message to have a calibration. If you confirm to do it, please click **OK**. If don't, click **Cancel**.

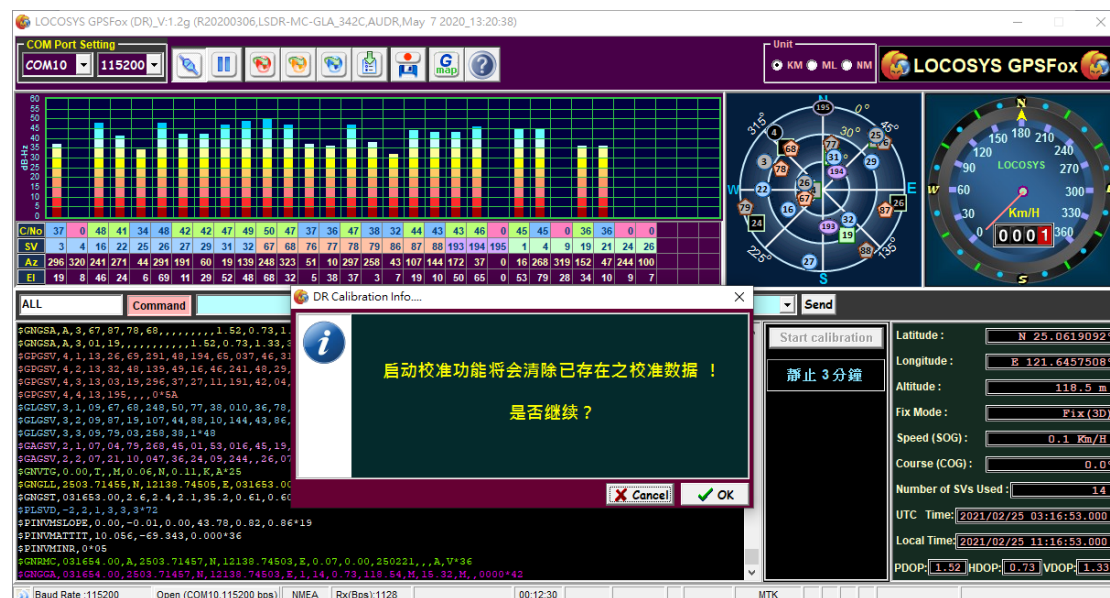


Figure 8: Message to have a calibration

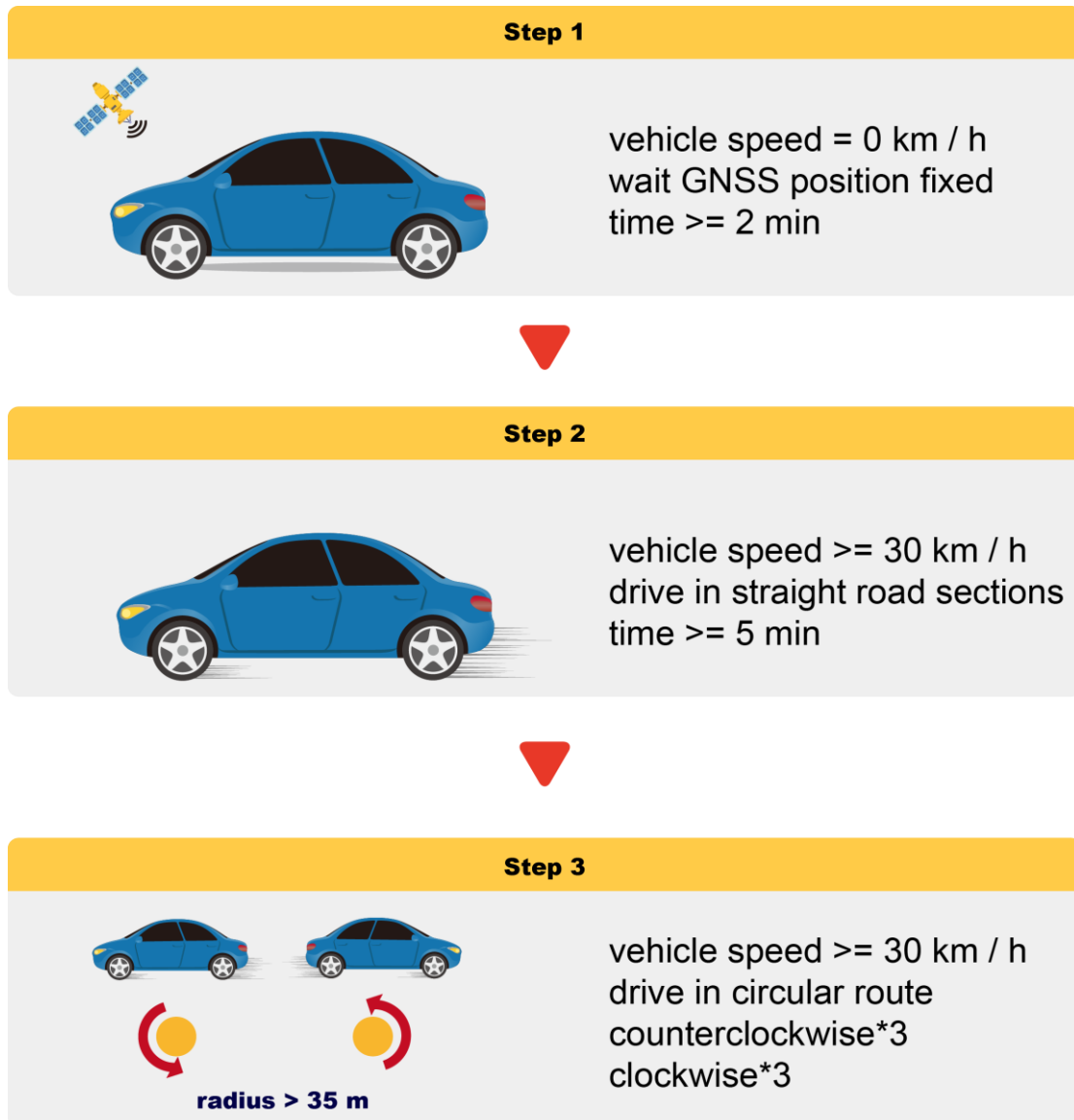


Figure 9: Calibration Flow Chart

The Inertial Status window below helps to confirm if the current inertial navigation is available.

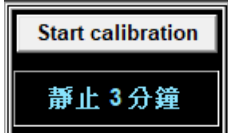

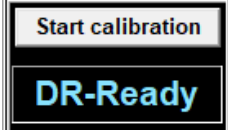
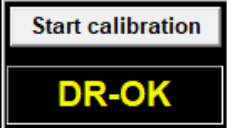
Calibration Status	GPSFox correspond display
\$PINVMINR,0*05  Not Initialized	
\$PINVMINR,1*04  Initializing	
\$PINVMINR,2*03  Calibrating	
\$PINVMINR,3*04  Calibration done	

Figure 10: Start Calibration

**Note:**

The calibration procedure provided above is the fastest and most accurate calibration method for inertial navigation. When the actual customer uses it, INS calibration can be done in normal driving habits.

Inertial navigation has a self-learning function. When the car continues to travel after the basic correction is completed, the inertial navigation will continue to calibrate the learning and converge the divergence of the route, thereby improving the reliability of the inertial navigation

9. If you want to save the Log file of NMEA data, please press “Start to Log data” button.

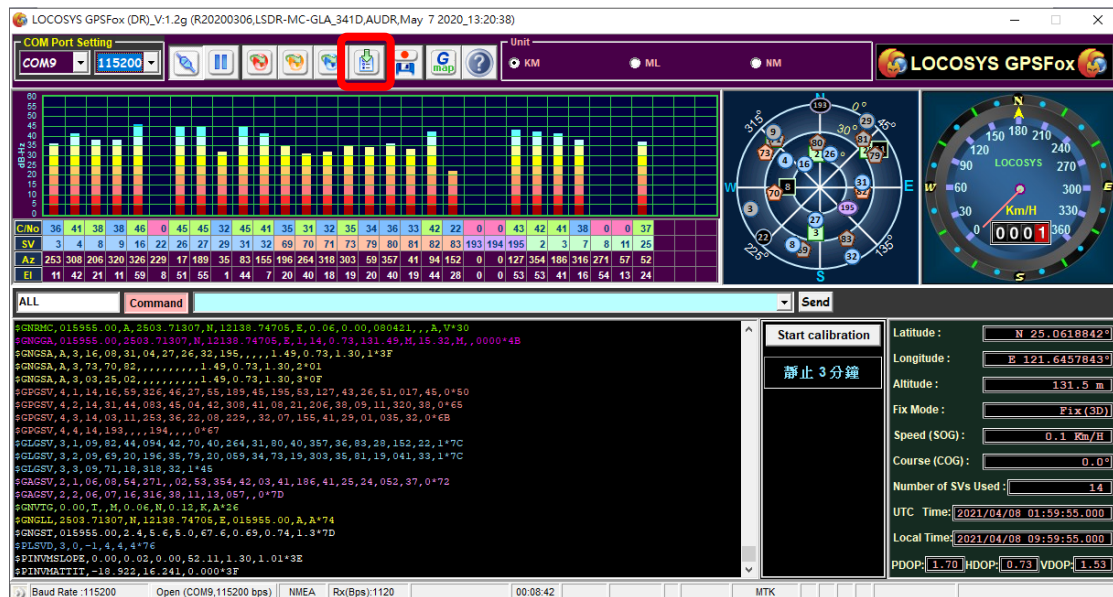


Figure 11: Start to Log data button

10. Please choose the file path where you want to save, and type a file name. Then please press “SAVE” button and it can start recording NMEA LOG Data.

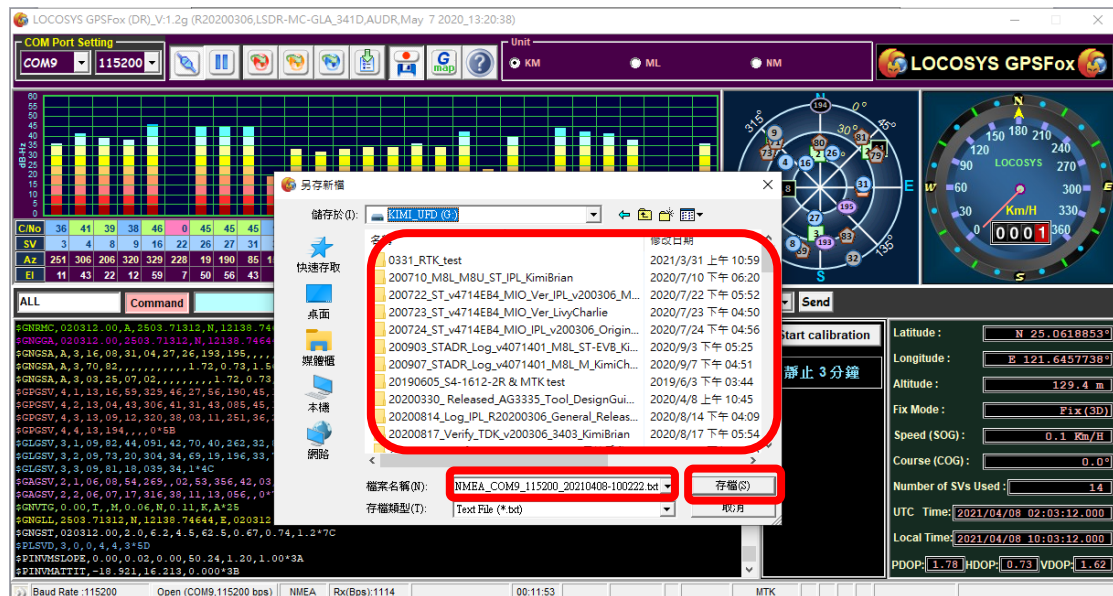
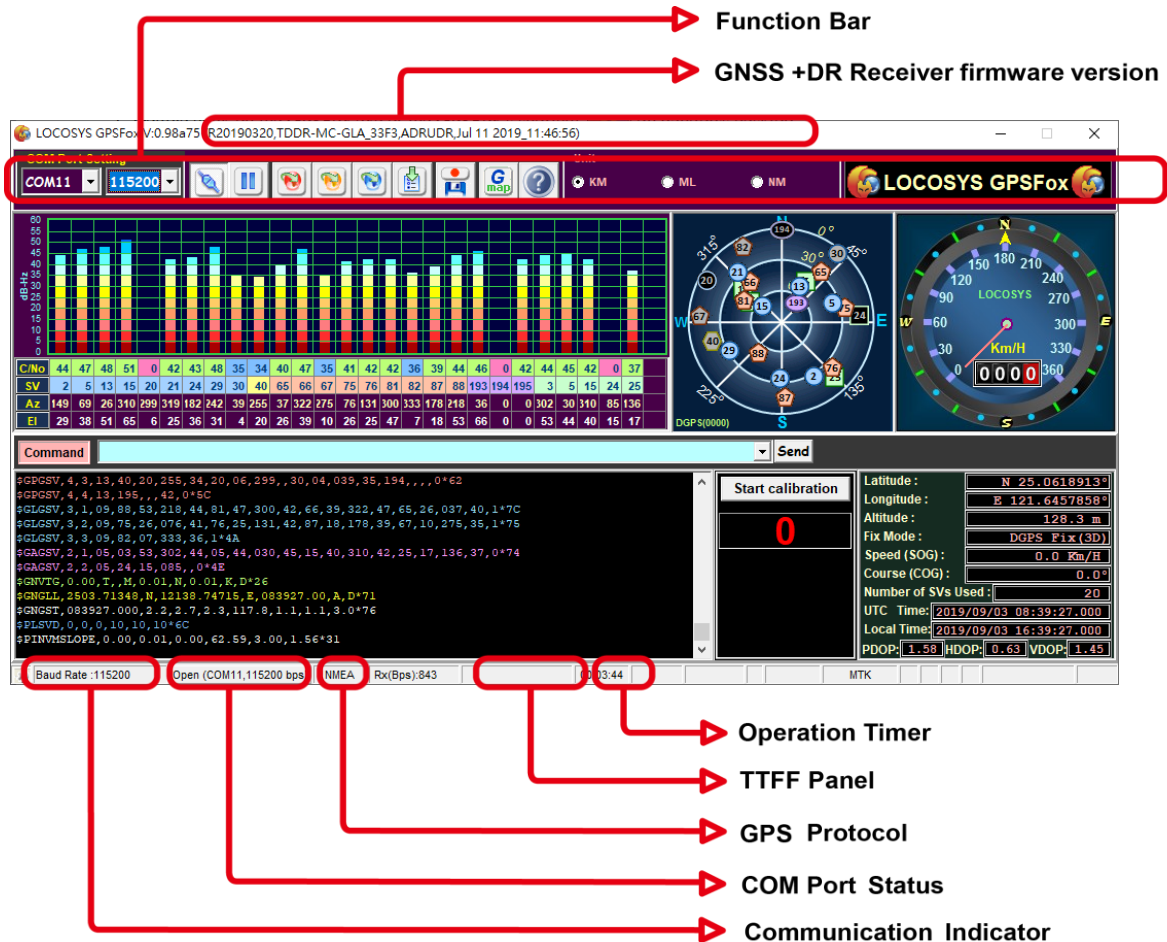


Figure 12: Press SAVE button

## 4. About the GPSFox

The GPSFox is an easy-to-use utility which can display graphically specific NMEA 0183 message received from GNSS receiver. There are five information areas, one



function bar and some status indicators in the main form.

Figure 13: GPSFox

The **Signal Level View** displays the satellite number(SV), azimuth(Az), elevation(EI) of tracked and available satellites in a text form. It also shows the C/No value in both text and graphical forms.



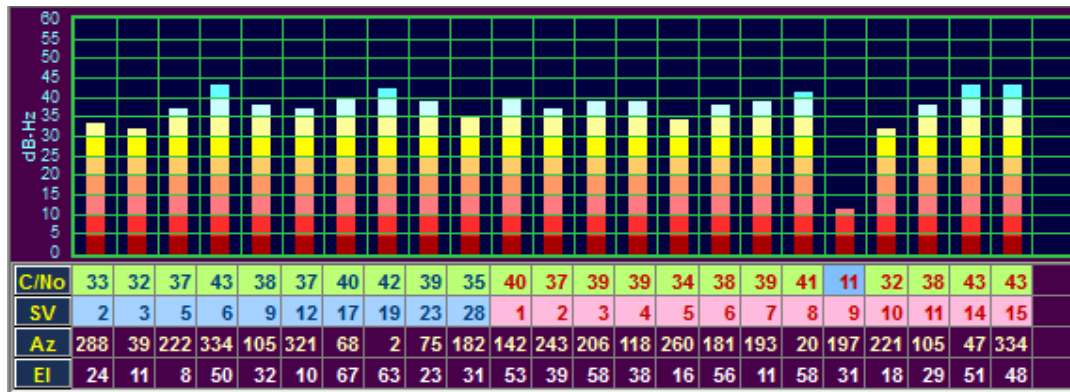


Figure 14: Signal Level View

The **Radar View** displays the azimuth and elevation of tracked and available satellites in a graphical form. The color of the satellite status is:

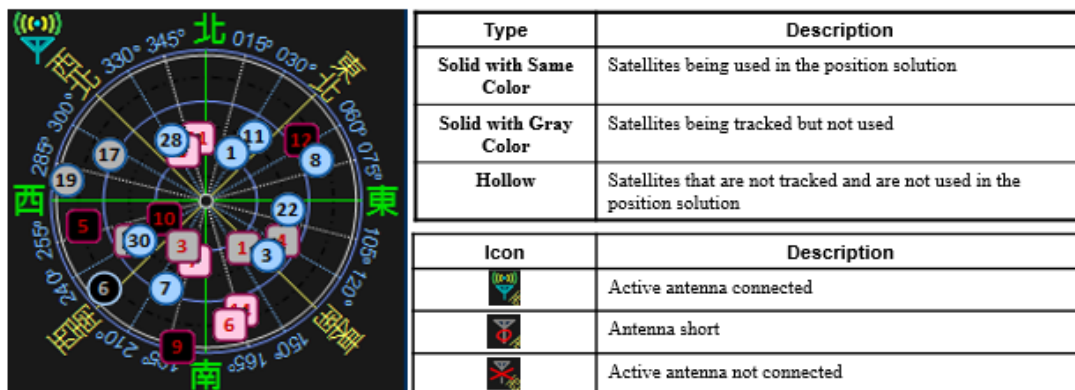


Figure 15: Radar View





Figure 16: COG&SOG View

The **COG&SOG View** displays the GNSS speed and direction in a graphical form. There are three measurement systems can be shown: Metric (Km), Imperial (Mile) or Nautical Mile (Knot). You can select the unit of measurement in the Unit selection box on **Function Bar** by click the item of Km, Mile or Knot.

```
$GPGLL,2503.7150,N,12138.7445,E,033806.000,A,D+5E
$GPGSA,A,3,24,26,21,09,18,29,27,10,15,,,1.29,1.00,0.82+09
$GPGSV,3,1,11,24,71,193,45,27,68,078,42,09,62,174,37,26,58,347,45+70
$GPGSV,3,2,11,42,54,141,38,21,52,303,44,15,47,023,43,18,25,313,41+7F
$GPGSV,3,3,11,10,25,093,40,29,15,224,37,12,04,168,+46
$GPRMC,033806.000,A,2503.7150,N,12138.7445,E,0.03,0.00,040509,,,D+62
$GPVTG,0.00,T,M,0.03,N,0.06,K,D+3D
$GPGGA,033807.000,2503.7150,N,12138.7445,E,2,9,1.00,128.8,M,15.3,M,0000,00
$GPGLL,2503.7150,N,12138.7445,E,033807.000,A,D+5F
$GPGSA,A,3,24,26,21,09,18,29,27,10,15,,,1.29,1.00,0.82+09
$GPGSV,3,1,11,24,71,193,45,27,68,078,42,09,62,174,37,26,58,347,45+70
$GPGSV,3,2,11,42,54,141,38,21,52,303,44,15,47,023,43,18,25,314,41+78
$GPGSV,3,3,11,10,25,093,40,29,15,224,37,12,04,168,+46
$GPRMC,033807.000,A,2503.7150,N,12138.7445,E,0.01,0.00,040509,,,D+61
$GPVTG,0.00,T,M,0.01,N,0.03,K,D+3A
```

Figure 17: NMEA View

The **NMEA View** displays the original NMEA messages received from GNSS receiver. If you want to clear the content of **NMEA View**, just right-click in **NMEA View** area and click the **Clear** item on popup menu.

Latitude :	N 25°03'42.815"
Longitude :	E 121°38'44.810"
Altitude :	120.1 m
Fix Mode :	3D
Speed (SOG) :	0.1 Km/H
Course (COG) :	39.5°
Number of SVs Used :	21
GPS Time:	2016/07/06 10:47:14.000
Local Time:	2016/07/06 18:47:14.000
PDOP:	1.07
HDOP:	0.62
VDOP:	0.88

The **Navigation View** displays the primary navigation information, the units of measurements are determined in the Unit selection box.

Fix Mode	Description
not Fix	Fix not available
2D	2D (<4 SVs used)
3D	3D (>3 SVs used)

Figure 18: Navigation View

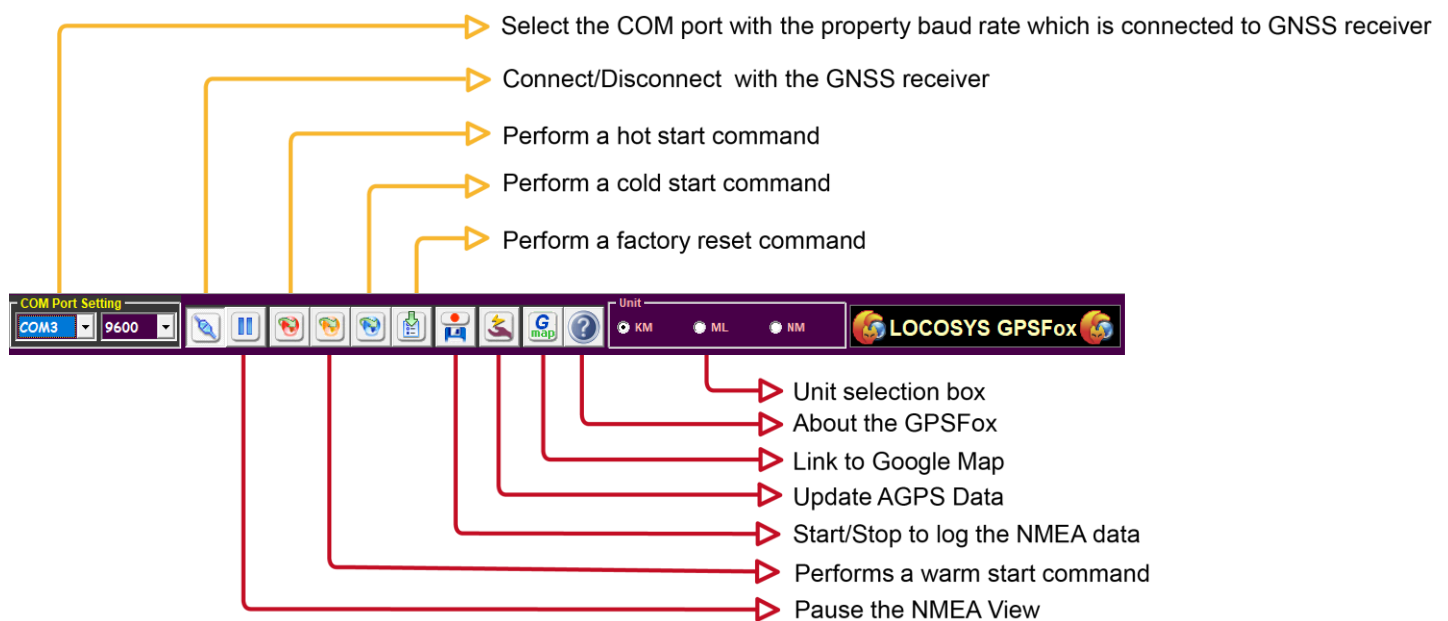


Figure 19: Function Bar



### : About the GPSFox

The firmware version can be found after left top LOCOSYS GPSFox's logo & version



Figure 20: About the GPSFox



### : Update AGPS data

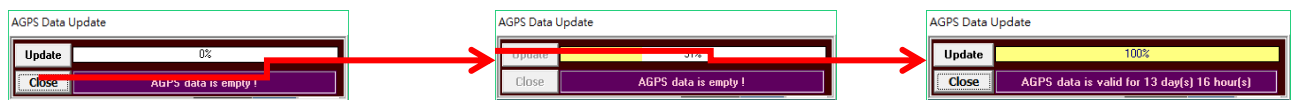


Figure 21: Update AGPS data

Clicks the AGPS button for updating EPO data. If AGPS function is enabled, GPSFox has automatically upload AGPS data to GNSS receiver. Therefore, the TTFF of cold start or warm start with AGPS will faster than them without AGPS aiding.

Desktop or laptop PC needs to connect with Internet when you evaluate the AGPS function.

### GNSS Receiver's Firmware version

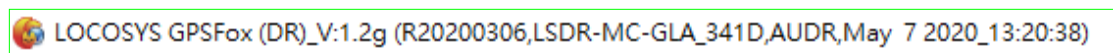


Figure 22: GNSS Receiver's Firmware version

# Command line Support:

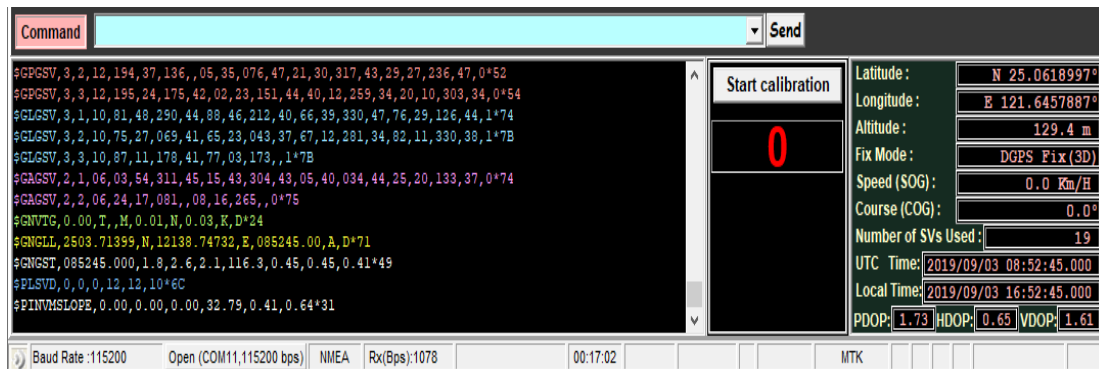


Figure 23: Command line

The version GPSFox can support manual input command. You need to call a hidden command line out. Hold Ctrl key and use mouse to click top right GPSFox logo. An input window will prompt up. Key in “**commandbox**” then clicks okay button. A hidden command line will come out.

You can use the command line to input HED proprietary binary command. Before you input HED binary command you should key in “**HEXCMD:**” for GPSFox accepting.

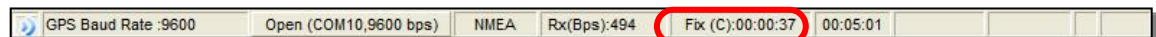


Figure 24: TTFF panel

If you perform a Hot/Warm/Cold Start command, the information of TTFF (Time To First Fix) will display on the TTFF panel.

## 5. FAQ (Trouble Shooting)

### 1. Why can't I open the google?

Ans :

- (1) Please check if your computer has been connected to the internet or not.
- (2) Please check if GNSS has been positioned.

### 2. Why does the screen only show NMEA messages without any color?

Ans :

It is because GPSFox cannot tell which firmware version of your products is.

- (1) For EVK: please unplug and re-plug your USB cable to connect GPSFox.
- (2) For GPS/GNSS Module: please check if “the RX pin of GPS/GNSS module” has been connected to “the TX pin of your own systems” already or not.

### 3. Why is there no “automotive speed”?

Ans :

- (1) **Firstly**, it needs to know if the source of the automotive speed is from ODO or UART.

- **ODO Way:**

1. From the 12V of the original automotive speed cable
2. Transfer PWM signals via MCU

- **UART Way:** Please use MCU to transfer the sentence output of “\$PSTMDRSENMSG”.

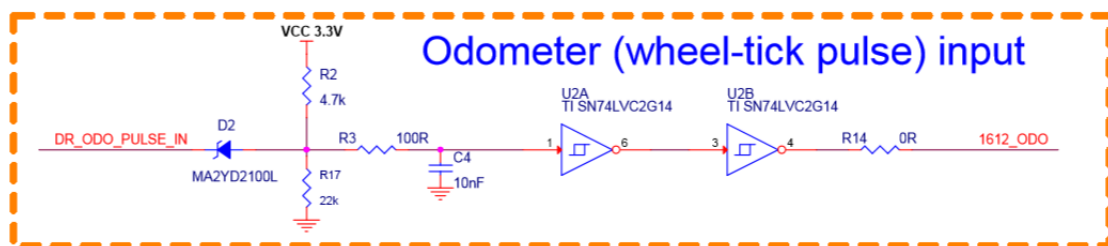
(2) **Secondly**, If the speed source is confirmed, then we can further check more details below respectively. The circuit diagram can be referred to the its corresponding datasheet.

## ● ODO Way

From the 12V of the original automotive speed cable:

Please check the circuit diagram and see if the circuit line has been connected into the module.

If the automotive speed does not connect to the Module directly via the below circuit line, it would cause Module damaged.



### i. Transfer PWM signals via MCU:

Please check if the program code of MCU has been written completely.

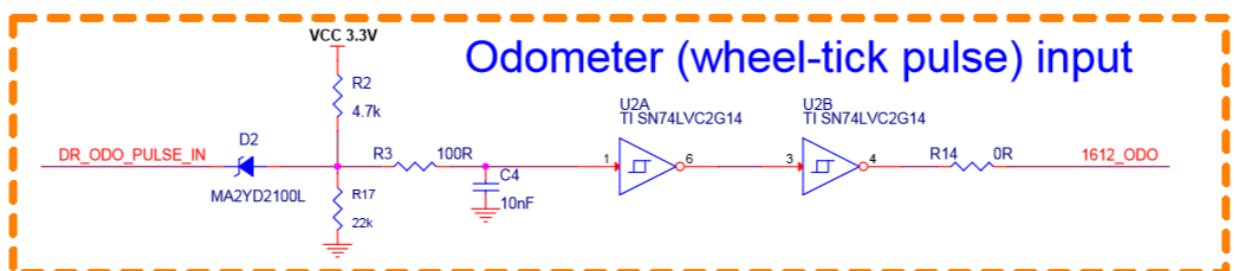
The calculation way of PWN is shown as below.

### ii. $\text{PWM (HZ)} = \text{Automotive Speed (km/h)} * 4$ ; duty cycle = 50%

### iii. PWN output must be kept in a linear way, such as automotive

speed:30km/h:PWM=120Hz;60km/h:PWM=240Hz;90km/h:PW

M=360Hz.Besides, please also check the circuit diagram and see if this circuit line has been connected into the module.



## ● UART Way

Please check if the sentence output of “\$PSTMDRSENMSG” is correct or not.

### PSTMDRSENMSG---Sensor data over UART

Customer needs get vehicle speed from the microprocessor and follow the table's data format to input MC-1612-DX module.

Table 11.2-7 contains the values for the following example:

\$PSTMDRSENMSG,14,0,31\*16

Table 11.2-7 \$ PSTMDRSENMSG Data Format

Name	Example	Units	Description
Message ID	\$PSTMDRSENMSG		\$PSTMDRSENMSG protocol header
MSG ID	14		Data type
MSG ID	0		Data type
Microprocessor output speed	31	Km/h	Speed over ground in kilometers per hour
Checksum	*16		
<CR> <LF>			End of message termination

Note: Default recommend input up to 5Hz to module pin14.

## 4. Why does the calibration take so long for some modules?

Ans:

The calibration needs to consider “the set-up way of tested object”, “the routes environment of calibration”, and “speed”. Even if you go the same route with the same speed, the calibration time will be more or less differently according to the environment interference in that period. What we can control is the set-up way and the car-driving way under calibration. As long as you can follow previous provided set-up and calibration way, it can make the calibration of the tested object be completed as soon as possible.

### 5. How to teach the car owner to calibrate?

Ans:

The above calibration steps are the fastest and the most correct calibration way.

When your customers use it, please just follow the usual driving habits, then the dead reckoning calibration can be completed.

### 6. How to check if Dead Reckoning function works or not?

Ans:

When the calibration of the tested object is completed, please disconnect the signals and observe if the positioning status of GGA sentence is 6. If it is, it means the Dead Reckoning assisted function has already started. Please refer to the below sentence.

(\$GNGGA,062026.000,2503.52320,N,12137.30974,E,6,18,0.6,038.24,M,15.3,M,,\*7A)

### 7. Why is the evaluation result not good after calibration?

Ans:

Dead Reckoning has automatically learning function. After completing the basic calibration, the Dead Reckoning will continue learning calibration and make the moving trajectory more and more precise. It can raise the reliability of Dead Reckoning. Therefore, when you finish calibration, it will be suggested not to hurry to test and do more calibrations instead. More calibrations will be helpful for your evaluation result.

