



Vector H102 GPS Compass OEM Board Integrator Guide

Part No. 875-0280-000 Rev D1



www.hemispheregps.com



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Contents

Chapter 1	Introduction	1
	Overview	2
	Configuring the H102	3
	Message Interface	3
	Using VectorPC to Communicate with the H102	3
Chapter 2	Layout and Connectors	5
	Mechanical Layout	6
	Connectors	7
Chapter 3	Installation	9
	Creating an Enclosure	10
	Mounting the Board	10
	Plastic Cover	10
	Mounting Location	12
	GPS Reception	12
	H102 Environmental Considerations	12
	VHF Interference	12
	Mounting Orientation	14
	Shielding the H102	16
	Powering the H102	16
	Power Considerations	16
	Connecting to a Power Source	16
	Electrical Isolation	16
	Connecting to External Devices	17
	J60 Pinouts	17
	J60 Signals	19
	Ports	20
	Serial Ports	20
	NMEA 2000 Port	21
	Default Parameters	25
	Standard Configuration	25
Chapter 4	Operation	27
	GPS Overview	28
	GPS Operation	28
	Differential Operation	29
	H102 Overview	29
	Fixed Baseline Moving Base Station RTK	29
	Supplemental Sensors	30

Time Constants	32
Watchdog	33
Common Commands and Messages	33
Appendix A Troubleshooting	37
Appendix B Technical Specifications	41
Index	45
End User License Agreement	47
Warranty Notice	50

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Chapter 1: Introduction

Overview

Configuring the H102

Message Interface

Using VectorPC to Communicate with the H102

The purpose of this chapter is to help you get the H102 running quickly; however, it is not intended to replace the balance of this manual and it assumes a reasonable amount of knowledge of GPS navigation system installation. Novice GPS and SBAS users should consult Chapter 4, “Operation” and the Hemisphere GPS Technical Reference (go to www.hemispheregps.com and click the GPS Reference icon) for further information on these services and technologies.

Note: The term “machine” is used throughout this manual as a general term for a vessel, craft, boat, vehicle, etc.

Overview

The Vector H102™ GPS Compass OEM Board is based upon Hemisphere GPS’ exclusive Crescent® and Crescent Vector™ II technologies.

Note: Throughout this manual, the Vector H102 GPS Compass OEM Board is referred to simply as the H102.

The H102 is a complete GPS compass and positioning system that requires only one power/data cable connection (see “Powering the H102” on page 16 and “Connecting to External Devices” on page 17 for more information). With its CAN support and ease of installation, the H102 is the perfect solution for both marine and land-based applications such as mine construction, earthworks, and machine guidance.

The H102, included in marketing kit part number 940-3050-000, is an integrated system comprised of the following:

- Crescent Vector II technology
- Dual integrated GPS antennas
- Power supply
- Single axis gyro
- Tilt sensor on each axis (X and Y axes)

The gyro and tilt sensors are present to improve system performance and to provide backup heading information in the event that a GPS heading is not available due to signal blockage.

Crescent Vector II technology supports multiple RF front ends—enabling tighter coupling of measurements from separate antennas for use in heading-based products. Users will achieve excellent accuracy and stability due to Crescent’s more accurate code phase measurements, improved multipath mitigation, and fewer components.

The H102’s GPS antennas are separated by 27.5 cm between their phase centers, resulting in better than 0.75° rms heading performance. The H102 provides heading and positioning updates of up to 20 Hz and delivers positioning accuracy of better than 1.0 m 95% of the time when using differential GPS corrections from Space Based Augmentation Systems (SBAS).

H102 also features Hemisphere GPS’ exclusive COAST™ technology that enables Hemisphere GPS receivers to utilize aging differential GPS correction data for 40 minutes or more without significantly affecting positioning quality. H102 is less likely to be affected by differential signal outages due to signal blockages, weak signals, or interference when using COAST.

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S

securing the enclosure 10
 sensor specifications 42
 settings, default 25
 signals 19
 SPDTAU 32, 36
 specifications
 communication 42
 environmental 43
 GPS sensor 42
 mechanical 43
 power 43
 speed time constant 32
 supplemental sensors 30

T

tilt aiding 30
 time constants 32
 COGTAU 32
 HRTAU 32
 HTAU 32
 PTAU 32
 SPDTAU 32
 tracking
 automatic 28
 automatic SBAS 29
 troubleshooting 38

V

VHF interference 12

W

watchdog 33

Configuring the H102

The H102 offers either serial port or NMEA 2000 port functionality and comes preconfigured. You only need to do the following to begin using the H102:

- Connect the H102 to a power supply
See “Powering the H102” on page 16
- Set up your COM ports
See “Ports” on page 20
- Make sure the H102 has a clear view of the sky
- Connect the H102 to a PC running VectorPC and then set up VectorPC (to track satellites set up the GPGLGA and GPGLSV messages)
See “Using VectorPC to Communicate with the H102” below

Note: The H102 provides limited CAN support. For more information contact Hemisphere GPS Technical Support.

Message Interface

The H102 uses a NMEA 0183 interface, allowing you to easily make configuration changes by sending text-type commands to the receiver.

The H102 also supports a selection of binary messages including NMEA 2000. There is a wider array of information available through the binary messages, plus binary messages are inherently more efficient with data. If the application has a requirement for raw measurement data, this information is available only in a binary format.

For more information on NMEA 0183 commands and messages as well as binary messages (and NMEA 2000 messages) refer to the Hemisphere GPS Technical Reference (go to www.hemispheregps.com and click the GPS Reference icon).

Using VectorPC to Communicate with the H102

Hemisphere’s VectorPC is a free utility program that runs on your Windows PC or Windows mobile device. Simply connect your Windows device to the H102 via the COM port and open VectorPC. The screens within VectorPC allow you to easily interface with the H102 to:

- Select the internal SBAS, beacon, or L-band correction source and monitor reception (beacon and L-band optional)
- Configure NMEA messages, Vector parameters, and port settings
- Monitor Vector performance and tracking information
- Review heading, pitch, and roll visually
- Automatically calculate heading bias

VectorPC is available for download from the Hemisphere GPS website (www.hemispheregps.com).

Index

A

- aiding
 - gyro 31
 - tilt 30
- alarm, watchdog 33
- automatic
 - SBAS tracking 29
 - tracking 28

B

- board mounting 10

C

- COGTAU 32, 36
- commands (common) 33
- common commands and messages 33
- communication specifications 42
- configuration 3
- connecting
 - to a power source 16
 - to external devices 17
- connectors 7
 - mating 7
 - OEM board 7
- course over ground time constant 32

D

- default settings 25
- designing the enclosure 10

E

- electrical isolation 16
- enclosure
 - board mounting 10
 - creating 10
 - designing 10
 - securing 10
- environmental
 - considerations 12
 - specifications 43
- environmental considerations 12
- external devices 17

G

- GPHEV 14, 34
- GPS
 - automatic SBAS tracking 29
 - automatic tracking 28
 - operation 28
 - overview 28

- receiver performance 28
 - sensor specifications 42
- GPS reception 12
- gyro aiding 31

H

- heading rate time constant 32
- heading time constant 32
- heave 14, 34
 - accuracy 42
- HRTAU 32, 36
- HTAU 32, 36

I

- interfacing to a PC 21

L

- layout (mechanical) 6

M

- mechanical layout 6
- mechanical specifications 43
- messages (common) 33
- mounting
 - environmental considerations 12
 - GPS reception 12
 - location 12
 - orientation 14
 - VHF interference 12
- moving base station RTK 29

O

- orientation for mounting 14

P

- parallel mounting 14
- perpendicular mounting 14
- pinouts 18
- pitch time constant 32
- power specifications 43
- powering
 - connecting to a power source 16
 - electrical isolation 16
- PTAU 32, 36

R

- receiver performance 28
- RS-232 42



Chapter 2: Layout and Connectors

Mechanical Layout
Connectors

Mechanical Layout

Figure 2-1 shows the H102's mechanical layout. All dimensions are in millimeters.

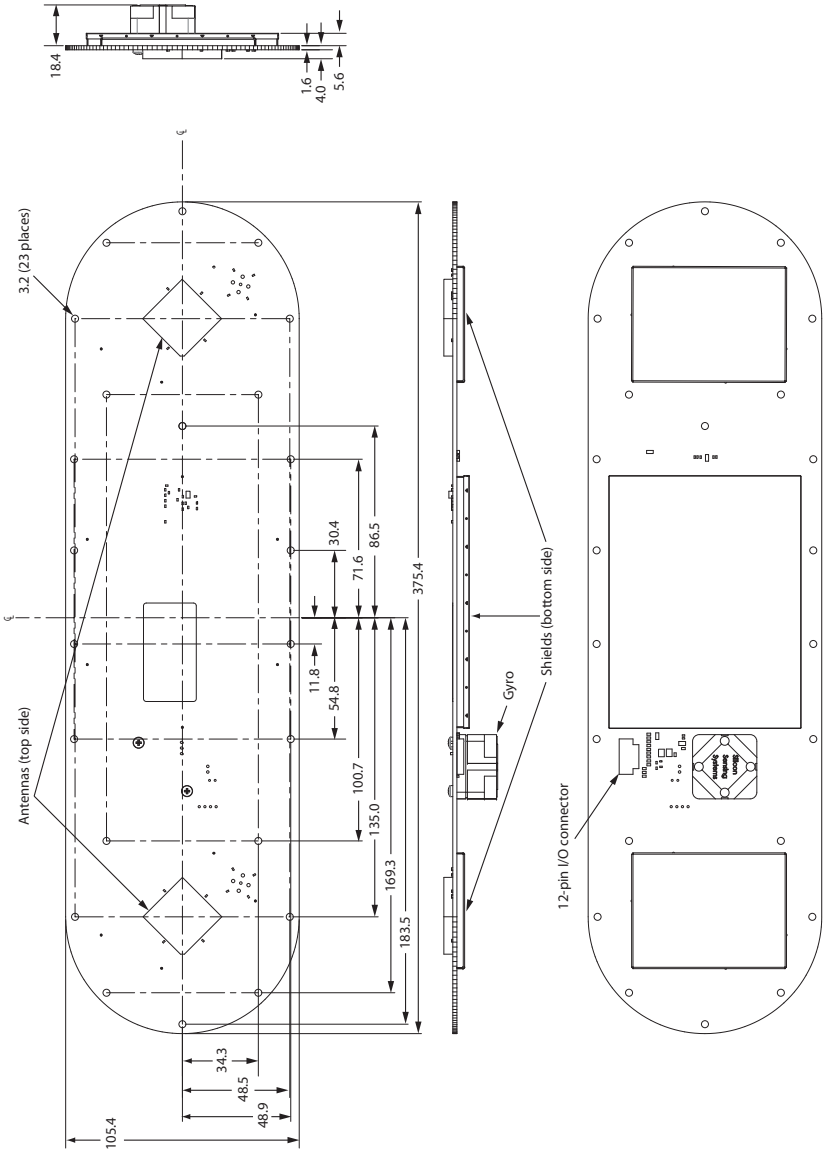


Figure 2-1: H102 OEM board layout

Table B-3: Power specifications

Item	Specification
Input voltage	6 to 36 VDC
Power consumption	3 W nominal
Current consumption	320 mA @ 9 VDC 240 mA @ 12 VDC 180 mA @ 16 VDC
Power isolation	Isolated to ground
Reverse polarity protection	Yes

Table B-4: Mechanical specifications

Item	Specification
Dimensions (not including mounts)	37.5 L x 10.5 W x 2.5 H (cm) 14.8 L x 4.1 W x 1.0 H (in)
Weight	250 g (8.8 oz)

Table B-5: Environmental specifications

Item	Specification
Operating temperature	-30°C to +70°C (-22°F to +158°F)
Storage temperature	-40°C to +85°C (-40°F to +185°F)
Humidity	95% non-condensing (when installed in an enclosure)
Vibration	IEC 60945 (when mounted in an enclosure with screw mounting holes utilized)
EMC	FCC Part 15, Subpart B, CISPR22, CE

¹Depends on multipath environment, number of satellites in view, satellite geometry, ionospheric activity, and use of SBAS

²Depends on multipath environment, number of satellites in view, satellite geometry, and ionospheric activity

³Based on a 40-second time constant

⁴This is the minimum safe distance measured when the product is placed in the vicinity of the steering magnetic compass. The ISO 694 defines "vicinity" relative to the compass as within 5 m (16.4 ft) separation.

⁵Hemisphere GPS proprietary

Table B-1 through Table B-5 provide the H102's GPS sensor, communication, power, mechanical, and environmental specifications.

Table B-1: GPS sensor specifications

Item	Specification
Receiver type	L1, C/A code with carrier phase smoothing
Channels	Two 12-channel, parallel tracking (Two 10-channel when tracking SBAS)
SBAS tracking	2-channel, parallel tracking
Update rate	Standard 10 Hz, optional 20 Hz (position and heading)
Horizontal accuracy	< 1.0 m 95% confidence (DGPS ¹) < 2.5 m 95% confidence (autonomous, no SA ²)
Heading accuracy	< 0.75° rms Normal operation: GPS Coasting (no GPS): Gyro
Heave accuracy	< 30 cm rms ³ Normal operation: GPS Coasting (no GPS): None
Pitch accuracy	< 1.5° rms Normal operation: GPS Coasting (no GPS): Inertial sensor
Roll accuracy	< 1.5° rms using accelerometer Normal operation: Inertial sensor Coasting (no GPS): Inertial sensor
Rate of turn	90°/s maximum
Cold start	< 60 s typical (no almanac or RTC)
Warm start	< 20 s typical (almanac and RTC)
Hot start	< 1 s typical (almanac, RTC, and position)
Heading fix	< 10 s typical (valid position)
Compass safe distance	30 cm ⁴ (when installed in an enclosure)
Maximum speed	1,850 kph (999 kts)
Maximum altitude	18,288 m (60,000 ft)

Table B-2: Communication specifications

Item	Specification
Serial ports	2 full-duplex RS-232
Baud rates	4800, 9600, 19200, 38400, 57600, 115200
Correction I/O protocol	RTCM SC-104
Data I/O protocol	NMEA 0183, Crescent binary ⁵ , NMEA 2000
Timing output	1PPS, CMOS, active high, rising edge sync, 10 k Ω , 10 pF load

Connectors

Table 2-1 provides information on the J60 connector as well as related mating connectors. You can use different compatible connectors; however, the requirements may be different.

Table 2-1: H102 connectors

Connector	OEM Board Connector	Mating Connector
J60	ZIF FPC 12-pin	Use flexible cable

⚠ WARNING: Never add, remove, change, or short circuit any H102 jumpers. Doing so may cause undesirable effects and may damage the board. Always leave jumpers in their default positions, as shipped from the factory.



Appendix B: Technical Specifications



Chapter 3: Installation

Creating an Enclosure

Mounting Location

Mounting Orientation

Shielding the H102

Powering the H102

Connecting to External Devices

Ports

Default Parameters

Creating an Enclosure

Mounting the Board

The H102 has multiple mounting holes (in the gold/yellow band) available for securing the H102 to its enclosure (see Figure 3-1). Use all the mounting holes to make sure the H102 is securely fastened to the enclosure and structurally rigid. Hemisphere GPS recommends using all the mounting holes for your installation.

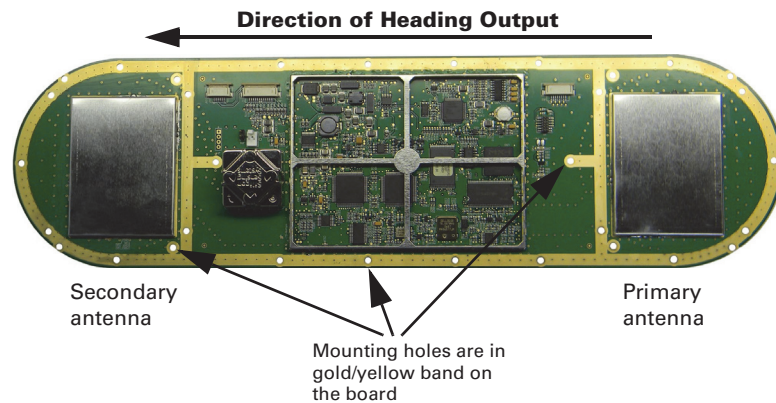


Figure 3-1: Board mounting

You can secure the board from the top or bottom. You must mount the board with the antennas facing upward (toward the sky).

Use self-tapping Plastite® Torx screws, 4-20 x 0.375, with a metal washer when securing the H102 to a plastic enclosure. If you are mounting the board to a material other than plastic, make sure you use an appropriate screw to properly secure the board.

Note: Make sure you properly ground the board on the mounting holes to signal ground.

Plastic Cover

For the plastic cover, Hemisphere GPS recommends using a high quality ASA copolymer (with no metal) with excellent weatherability, good flow, aesthetics, and high impact resistance. You can paint the plastic, but do not use a metallic paint.

A plastic cover over the antennas is mandatory when designing the enclosure. The enclosure must be within the antennas' reactive near field (see Figure 3-2 on page 11). The plastic cover over the antennas shifts the center frequency of the antennas to the GPS L1 frequency. The H102's GPS antennas are tuned to a frequency higher than the GPS L1 central frequency and require the plastic cover to be placed over the antennas

Table A-1: Troubleshooting (continued)

Symptom	Possible Solution
No heading or incorrect heading value	<ul style="list-style-type: none"> Check CSEP value is fairly constant without varying more than 1 cm (0.39 in)—larger variations may indicate a high multipath environment and require moving the receiver location Ensure MSEP is set to 0.275 m Verify all the settings in the \$JSHOW and \$JATT,SUMMARY command responses with the parameters shown in "Standard Configuration" on page 25 Recalibrate the tilt sensor with \$JATT,TILTCAL command if heading is calculated then lost at consistent time intervals Do not use the H102 under a reradiator; the H102 must be outside to provide heading with good GPS visibility (see Warning on page 28) Heading is from primary GPS antenna to secondary GPS antenna, so the arrow on the underside of the H102 should be directed to the bow side \$JATT,SEARCH command forces the H102 to acquire a new heading solution (unless gyro is enabled) Enable GYROAID to provide heading for up to three minutes during GPS signal loss Enable TILTAID to reduce heading search times Monitor the number of satellites and SNR values for both antennas within VectorPC—at least four satellites should have strong SNR values Potentially, the volume of data requested to be output by the H102 could be higher than the current baud rate supports (try using 19200 as the baud rate for all devices or reduce the amount of data being output)
No DGPS position in external RTCM mode	<ul style="list-style-type: none"> Verify the baud rate of the RTCM input port matches the baud rate of the external source Verify the pinout between the RTCM source and the RTCM input port (transmit from the source must go to receive of the RTCM input port and grounds must be connected) Ensure corrections are being transmitted to the correct port—using the \$JDIF,PORTC command on Port A will cause the receiver to expect the corrections to be input through Port C

Table A-1 provides troubleshooting for common problems.

Table A-1: Troubleshooting

Symptom	Possible Solution
Receiver fails to power	<ul style="list-style-type: none"> Verify polarity of power leads Check integrity of power cable connectors Check power input voltage (6 to 36 VDC) Check current restrictions imposed by power source (minimum available should be > 1.0 A)
No data from H102	<ul style="list-style-type: none"> Check receiver power status to ensure the receiver is powered (an ammeter can be used for this) Verify desired messages are activated (using VectorPC or \$JSHOW in any terminal program) Ensure the baud rate of the H102 matches that of the receiving device Check integrity and connectivity of power and data cable connections
Random data from H102	<ul style="list-style-type: none"> Verify the RTCM or binary messages are not being output accidentally (send a \$JSHOW command) Ensure the baud rate of the H102 matches that of the remote device Potentially, the volume of data requested to be output by the H102 could be higher than the current baud rate supports (try using 19200 as the baud rate for all devices or reduce the amount of data being output)
No GPS lock	<ul style="list-style-type: none"> Verify the H102 has a clear view of the sky Verify the lock status of GPS satellites (this can be done with VectorPC)
No SBAS lock	<ul style="list-style-type: none"> Verify the H102 has a clear view of the sky Verify the lock status of SBAS satellites (this can be done with VectorPC - monitor BER value) SBAS lock can only get if you are in an appropriate SBAS region (currently, there is limited SBAS availability in the southern hemisphere) Set SBAS mode to automatic with the \$JWAASPRN,AUTO command

no closer than 5 mm, with plastic no thicker than 3 mm. With the appropriate plastic enclosure the H102 will be properly tuned to track GPS.

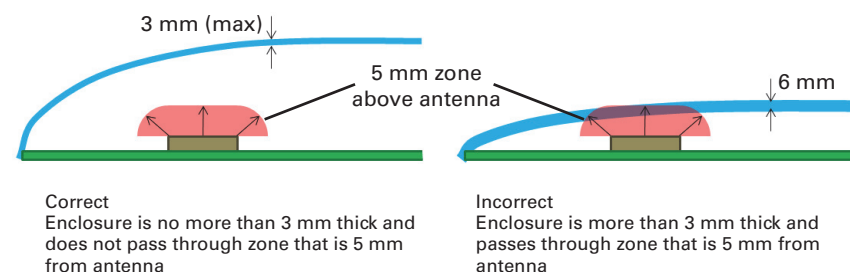


Figure 3-2: Plastic cover

In very benign RF environments, there may be no perceived positioning or heading performance difference between a system with or without a proper cover over the antennas. The broadcast GPS L1 signal has a 20 MHz bandwidth and the antennas capture only about 8 MHz of that signal. It is possible to achieve a functioning system with an offset central frequency; however, there will be reduced signal-to-noise (SNR) values as compared to an optimally design system.

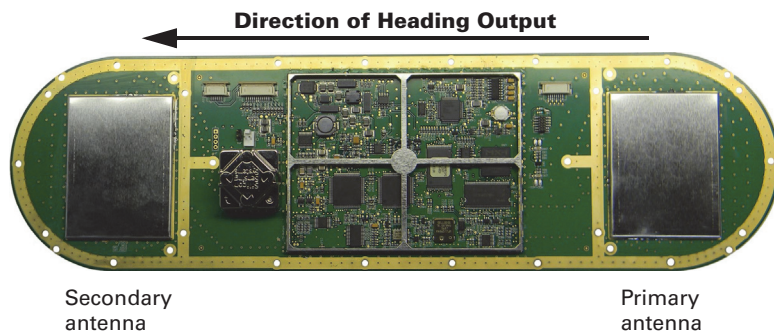
Mounting Location

This section provides information on determining the best location for the H102.

GPS Reception

When considering where to mount the H102, consider the following GPS reception recommendations:

- Consider GPS (and hence SBAS) reception, making sure the H102 has a clear view of the sky so the GPS and SBAS satellites are not masked by obstructions that may reduce system performance
- Since the H102 computes a position based on the internal primary GPS antenna element, mount the H102 where you desire a position with respect to the primary GPS antenna (it may be useful to put a directional marking in the plastics design of your enclosure to ease installation)



- Locate any transmitting antennas at least several feet away from the H102 to ensure tracking performance is not compromised, giving you the best performance possible
- Make sure there is enough cable length to reach a breakout box or terminal strip
- Do not locate the H102 where environmental conditions exceed those specified in Table B-5 on page 43

H102 Environmental Considerations

The H102 is designed to withstand harsh environmental conditions; however, adhere to the following limits when storing and using the H102:

- Operating temperature: -30°C to +70°C (-22°F to +158°F)
- Storage temperature: -40°C to +85°C (-40°F to +185°F)
- Humidity: 95% non-condensing (when installed in an enclosure)

VHF Interference

VHF interference from such devices as cellular phones and radio transmitters may interfere with GPS operation. When integrating with or near other transmitting RF devices consider interference from radio harmonics. For example, when integrating near marine radios consider the following:



Appendix A: Troubleshooting

Table 4-4: Binary messages (continued)

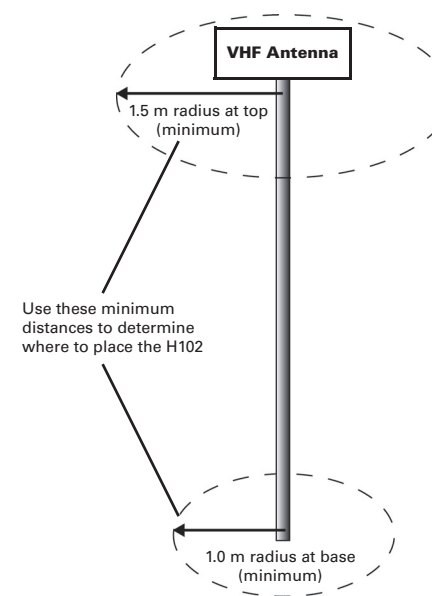
\$JBIN Message	Description
95	Satellite ephemeris data
96	Code and carrier phase
97	Processor statistics
98	Satellites and almanac
99	GPS diagnostics

Table 4-5: Parameters specific to \$JATT command

Parameter	Description	Query	Specify
COGTAU	Set/query COG time constant (0.0 to 3600.0 sec)	X	X
CSEP	Query antenna separation	X	
EXACT	Enable/disable internal filter reliance on the entered antenna separation	X	X
FLIPBRD	Turn the flip feature on/off	X	X
GYROAID	Enable/disable gyro	X	X
HBIAS	Set/query heading bias (-180.0° to 180.0°)	X	X
HELP	Show the available commands for GPS heading operation and status	X	
HIGHMP	Set/query the high multipath setting for use in poor GPS environments	X	X
HRTAU	Set/query ROT time constant (0.0 to 3600.0 sec)	X	X
HTAU	Set/query heading time constant (0.0 to 3600.0 sec)	X	X
LEVEL	Enable/disable level operation	X	X
MSEP	Manually set or query antenna separation	X	X
NEGTLT	Enable/disable negative tilt	X	X
NMEAHE	Change the HDG, HDM, HDT, and ROT message headers between GP and HE	X	X
PBIAS	Set/query pitch/roll bias (-15.0° to 15.0°)	X	X
PTAU	Set/query pitch time constant (0.0 to 3600.0 sec)	X	X
ROLL	Configure for roll or pitch GPS orientation	X	X
SEARCH	Force a new GPS heading search		X
SPDTAU	Set/query speed time constant (0.0 to 3600.0 sec)	X	X
SUMMARY	Display current Crescent Vector settings summary	X	
TILTAID	Enable/disable accelerometer, pre-calibrated	X	X
TILTCAL	Calibrate accelerometers		X

- VHF marine radio working frequencies (Channels 1 to 28 and 84 to 88) range from 156.05 to 157.40 MHz. The L1 GPS working center frequency is 1575.42 MHz. The bandwidth is +/- 2 MHz to +/- 10 MHz, which is dependent on the GPS antenna and receiver design.
- VHF marine radios emit strong harmonics. The 10th harmonic of VHF radio, in some channels, falls into the GPS working frequency band, which may cause the SNR of GPS to degrade significantly.
- The radiated harmonic signal strength of different brands/models varies.
- Follow VHF radio manufacturers' recommendations on how to mount their radios and what devices to keep a safe distance away.
- Handheld 5 W VHF radios may not provide suitable filtering and may interfere with the H102's operation if too close.

Before installing your integrated H102 device use the following diagram to ensure there are no nearby devices that may cause VHF interference.

**Figure 3-3: H102 distance from nearby VHF radios**

Mounting Orientation

Keep in mind your integrated H102 device and mounting location when determining your mounting orientation.

The H102 outputs heading, pitch, and roll readings regardless of antenna orientation. However, the relation of the antennas to the machine's axis determines whether you will need to enter a heading, pitch, or roll bias. The primary antenna is used for positioning and the primary and secondary antennas, working in conjunction, output heading, pitch, and roll values.

Note: Regardless of which mounting orientation you use, the H102 provides the ability to output the heave of the machine via the \$GPHEV message. For more information on this message refer to the Hemisphere GPS Technical Reference (go to www.hemispheregps.com and click the GPS Reference icon).

Parallel Orientation: The most common installation is to orient the H102 parallel to, and along the centerline of, the axis of the machine. This provides a true heading. In this orientation:

- If you use a gyrocompass, you can enter a heading bias in the H102 to calibrate the physical heading to the true heading of the machine.
- You may need to adjust the pitch/roll output to calibrate the measurement if the Vector is not installed in a horizontal plane.

Perpendicular Orientation: You can also install the antennas so they are oriented perpendicular to the centerline of the machine's axis. In this orientation:

- You will need to enter a heading bias of +90° if the primary antenna is on the starboard side of the machine and -90° if the primary antenna is on the port side of the machine.
- You will need to configure the receiver to specify the GPS antennas are measuring the roll axis using \$JATT,ROLL,YES.
- You will need to enter a roll bias to properly output the pitch and roll values.
- You may need to adjust the pitch/roll output to calibrate the measurement if the Vector is not installed in a horizontal plane.

Table 4-3: NMEA 0183 and other messages (continued)

Message	Info Type	Max Output Rate	Description	IEC Approved Message
\$GPRMC	P	20 Hz	Recommended minimum specific GNSS data	Yes
*\$GPROT	H	20 Hz	GPS-derived rate of turn (ROT) *see last bullet in Note at end of this table	Yes
\$GPRRE	S	1 Hz	Range residual and estimated position error	Yes
\$GPVTG	V	20 Hz	COG and ground speed	Yes
\$GPZDA	V	20 Hz	Time and date	Yes
\$PASHR	H	20 Hz	Time, heading, roll, and pitch data in one message	No
\$PSAT,GBS	S	1 Hz	Satellite fault detection (RAIM)	Yes
\$PSAT,HPR	H	20 Hz	Proprietary NMEA message that provides heading, pitch, roll, and time in single message	No
\$PSAT,INTLT	H	1 Hz	Proprietary NMEA message that provides the pitch and roll measurements from the internal inclinometers (in degrees)	Yes
\$RD1	S	1 Hz	SBAS diagnostic information	Yes
\$TSS1	H	20 Hz	Heading, pitch, roll, and heave message in the commonly used TSS1 message format	No

Notes:

- The GP of the message is the talker ID.
- GPGRS, GPGSA, GPGST, and GPGSV support external integrity checking. They are to be synchronized with corresponding fix data (GPGGA or GPGNS).
- For information on outputting roll, pitch, and heave data in one message refer to the Hemisphere GPS Technical Reference (go to www.hemispheregps.com and click the GPS Reference icon).
- *You can change the message header for the HDG, HDM, HDT, and ROT messages to either GP or HE using the \$JATT,NMEAHE command.
 - To preface these messages with GP, issue the following command:
\$JATT,NMEAHE,0<CR><LF>
 - To preface these messages with HE, issue the following command:
\$JATT,NMEAHE,1<CR><LF>
 For more information on the \$JATT,NMEAHE command refer to the Hemisphere GPS Technical Reference.

Table 4-4: Binary messages

\$JBIN Message	Description
1	GPS position
2	GPS DOPs
80	SBAS
93	SBAS ephemeris data
94	Ionosphere and UTC conversion parameters

Table 4-2: Commands (continued)

Command	Description
\$JRESET	Reset unit's configuration to firmware defaults Note: \$JRESET clears all parameters. For the H102 you will have to issue the \$JATT, FLIPBRD, YES command to properly redefine the circuitry orientation inside the product once the receiver has reset. Failure to do so will cause radical heading behavior. You can also issue the \$JRESET command with an optional field as follows: <ul style="list-style-type: none"> \$JRESET,ALL does everything \$JRESET does, plus it clears almanacs \$JRESET,BOOT does everything \$JRESET,ALL does, plus clears use of the real-time clock at startup, clears use of backed-up ephemeris and almanacs, and reboots the receiver when done
\$JSAVE	Save session's configuration changes

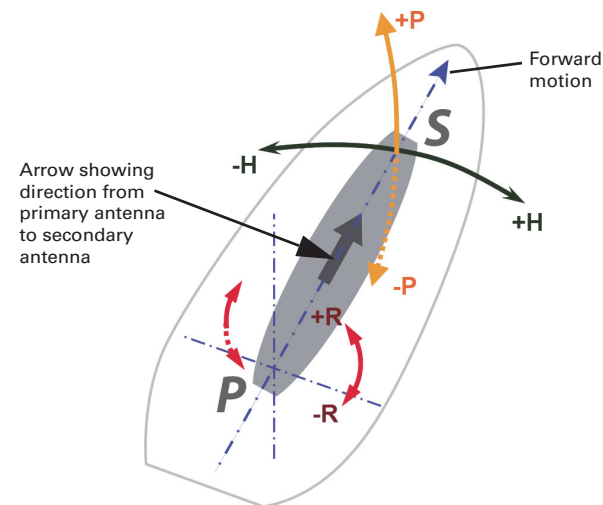
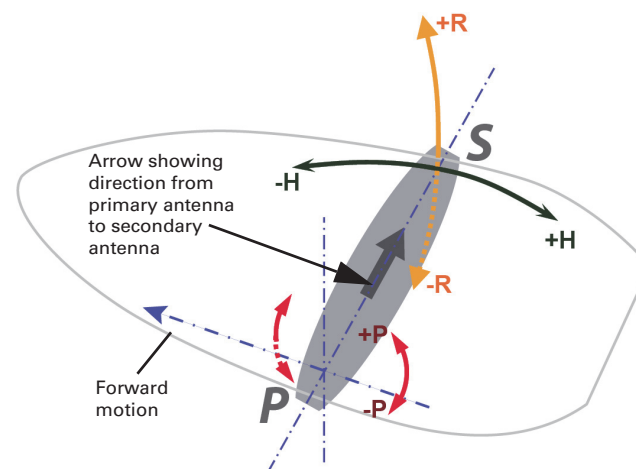
In Table 4-3 the Info Type value is one of the following:

- P = Position
- V = Velocity, Time
- H = Heading, Attitude
- S = Sats, Stats, Quality

Table 4-3: NMEA 0183 and other messages

Message	Info Type	Max Output Rate	Description	IEC Approved Message
\$GPD TM	P	1 Hz	Datum reference	Yes
\$GPGGA	P	20 Hz	GPS position and fix data	Yes
\$GPG LL	P	20 Hz	Geographic position - lat/long	Yes
\$GPG NS	P	20 Hz	GNSS position and fix data	Yes
\$GPG RS	S	1 Hz	GNSS range residual (RAIM)	Yes
\$GPG SA	S	1 Hz	GNSS DOP and active satellites	Yes
\$GPG ST	S	1 Hz	GNSS pseudo range error statistics and position accuracy	Yes
\$GPG SV	S	1 Hz	GNSS satellites in view	Yes
*\$GPH DG	H	20 Hz	Provides magnetic deviation and variation for calculating magnetic or true heading *see last bullet in Note at end of this table	Yes
*\$GPH DM	H	20 Hz	Magnetic heading (based on GPS-derived heading and magnetic declination) *see last bullet in Note at end of this table	No
*\$GPH DT	H	20 Hz	GPS-derived true heading *see last bullet in Note at end of this table	Yes
\$GPHEV	H	20 Hz	Heave value (in meters)	Yes

Figure 3-4 and Figure 3-5 provide mounting orientation examples.

**Figure 3-4: Recommended orientation and resulting signs of HPR values****Figure 3-5: Alternate orientation and resulting signs of HPR values**

Shielding the H102

There are three shields that are soldered to the H102:

- Two shields (one over each antenna LNA circuitry)
- One shield over the main circuitry

⚠WARNING: Under NO circumstances should you remove, mangle, destroy, tamper with, or otherwise pierce, puncture, or open any of these shields. Doing so can dramatically reduce receiver performance and will void the warranty.

⚠WARNING: Always follow proper electrostatic discharge protocols when handling the device. Avoid touching the PCB and its components directly with your fingers. Always grab onto the large metal shields on the device when handling the board.

Powering the H102

Power Considerations

For best performance use a clean and continuous power supply. The H102 power supply features reverse polarity protection but will not operate with reverse polarity.

See Table B-3 on page 43 for complete power specifications.

Connecting to a Power Source

Perform the following steps to connect to a power source:

1. Build mating connector to J60 on the H102.
 - If you will be operating in NMEA 2000 mode, Hemisphere GPS recommends a flex connector with a 5-pin mini NMEA 2000 connector.
 - If you will be operating in serial mode, Hemisphere GPS recommends a Conxall style serial connector.
 - Keep in mind that power for serial and NMEA 2000 is shared power.
2. Connect your wire to mating connector.

The H102 will start when you apply an acceptable voltage to the power leads of the extension cable.

⚠WARNING: Do not apply a voltage higher than 36 VDC as this will damage the receiver and void the warranty.

Electrical Isolation

The H102 features a power supply that is isolated from the communication lines.

Watchdog

The watchdog is a timer that is controlled by the software that monitors if the heading is lost. The watchdog software is compliant with IEC 60495.

Common Commands and Messages

Note: When selecting your baud rate and message types use the following formula and example to calculate the bits/sec for each message and then sum the results to determine the baud rate for your required data throughput.

The V103/113 has maximum baud rate of 38400.

*Message output rate * Message length (bytes) * bits in byte = Bits/second
(1 character = 1 byte, 8 bits = 1 byte, use 10 bits/byte to account for overhead)*

Example:

Message	Rate	Bytes	Bits in byte	Bits/sec
GPHDT	10	20	10	2000
GPROT	5	18	10	900
GPHDG	1	33	10	330
GPGGA	1	83	10	830
GPZDA	1	38	10	380
Total				4440

For information on message output rates refer to the Hemisphere GPS Technical Reference (go to www.hemispheregps.com and click the GPS Reference icon).

Table 4-2 below through Table 4-5 provide brief descriptions of common commands and messages for the H102. Refer to the Hemisphere GPS Technical Reference for more detailed information.

Table 4-2: Commands

Command	Description
\$JAGE	Specify maximum DGPS (COAST) correction age (6 to 8100 seconds)
\$JAPP	Query or specify receiver application firmware
\$JASC	Specify ASCII messages to output to specific ports (see ASCII messages in Table 4-3)
\$JBAUD	Specify RS-232, RS-422 (output) communication rate
\$JBIN	Specify binary messages to output to specific ports (see Table 4-4)
\$JDIFF	Query or specify differential correction mode
\$JGEO	Query or specify SBAS for current location and SBAS satellites
\$JI	Query unit's serial number and firmware versions
\$JOFF	Turn off all data messages
\$JQUERY,GUIDE	Query accuracy suitability for navigation

When enabled, the gyro is also used to update the post HTAU smoothed heading output from the moving base station RTK GPS heading computation—if the HTAU value is increased while gyro aiding is enabled, there will be little to no lag in heading output due to machine maneuvers. The Hemisphere GPS Technical Reference includes information on setting an appropriate HTAU value for the application.

Time Constants

The H102 incorporates user-configurable time constants that can provide a degree of smoothing to the heading, pitch, rate of turn (ROT), course over ground (COG), and speed measurements. You can adjust these parameters depending on the expected dynamics of the machine. For example, increasing the time is reasonable if the machine is very large and is not able to turn quickly or would not pitch quickly. The resulting values would have reduced 'noise,' resulting in consistent values with time. However, if the machine is quick and nimble, increasing this value can create a lag in measurements. Formulas for determining the level of smoothing are located in the Hemisphere GPS Technical Reference (go to www.hemispheregps.com and click the GPS Reference icon). If you are unsure on how to set this value, it is best to be conservative and leave it at the default setting.

Note: For heading and rate of turn there is no lag once the gyro is calibrated and enabled.

Heading time constant: Use the \$JATT,HTAU command to adjust the level of responsiveness of the true heading measurement provided in the \$GPHDT message. The default value of this constant is 10.0 seconds of smoothing when the gyro is enabled. The gyro is enabled by default, but can be turned off. By turning the gyro off, the equivalent default value of the heading time constant would be 0.5 seconds of smoothing. This is not automatically done so you must manually enter it. Increasing the time constant increases the level of heading smoothing and increases lag.

Pitch time constant: Use the \$JATT,PTAU command to adjust the level of responsiveness of the pitch measurement provided in the \$PSAT,HPR message. The default value of this constant is 0.5 seconds of smoothing. Increasing the time constant increases the level of pitch smoothing and increases lag.

Rate of Turn (ROT) time constant: Use the \$JATT,HRTAU command to adjust the level of responsiveness of the ROT measurement provided in the \$GPROT message. The default value of this constant is 2.0 seconds of smoothing. Increasing the time constant increases the level of ROT smoothing.

Course Over Ground (COG) time constant: Use the \$JATT,COGTAU command to adjust the level of responsiveness of the COG measurement provided in the \$GPVTG message. The default value of this constant is 0.0 seconds of smoothing. Increasing the time constant increases the level of COG smoothing. COG is computed using only the primary GPS antenna and its accuracy depends upon the speed of the machine (noise is proportional to 1/speed). This value is invalid when the machine is stationary, as tiny movements due to calculation inaccuracies are not representative of a machine's movement.

Speed time constant: Use the \$JATT,SPDTAU command to adjust the level of responsiveness of the speed measurement provided in the \$GPVTG message. The default value of this constant is 0.0 seconds of smoothing. Increasing the time constant increases the level of speed measurement smoothing.

Connecting to External Devices

This section provides information on connecting to other devices via J60.

J60 Pinouts

Figure 3-6 shows a schematic of the section of the H102 OEM board related to J60.

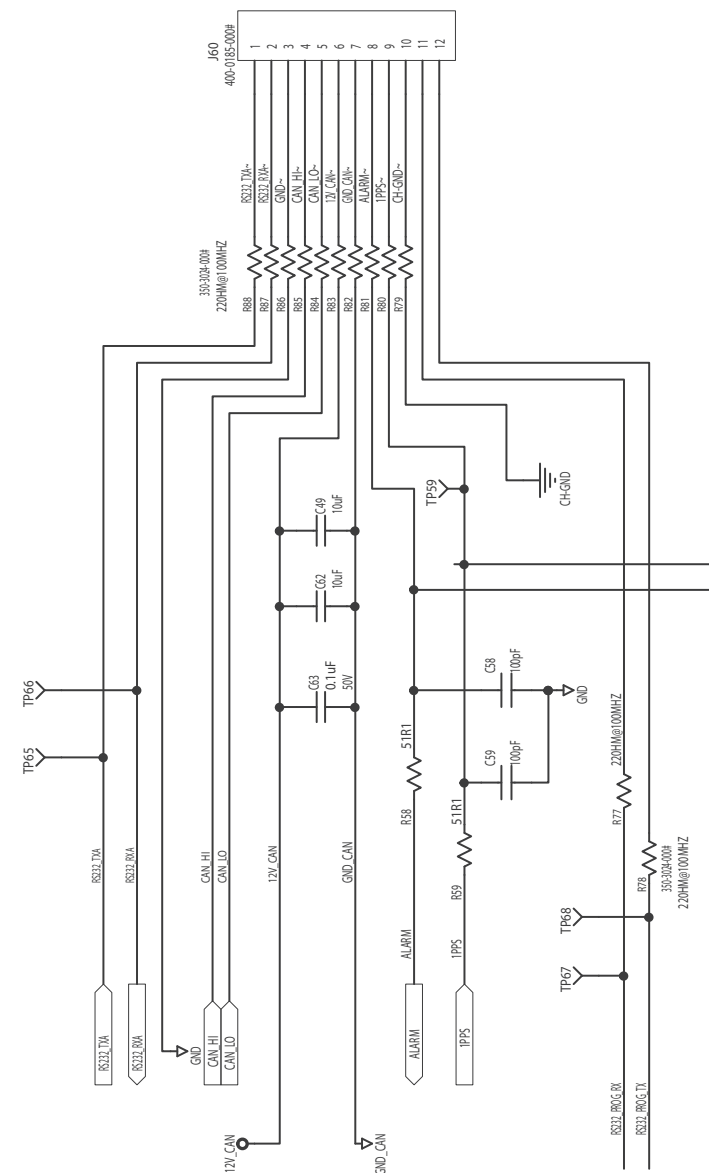


Figure 3-6: H102 schematic (board section related to J60)

Table 3-1 describes the J60 pinouts.

Note: Although a 12-pin connector is included with the H102 and the connector supports both CAN and serial, you can only use one mode at a time (CAN or serial) not both at the same time (this satisfies NMEA 2000 compliance).

Table 3-1: J60 pinouts

Pin	Description
1	Tx Port A, RS-232 (Output from H102)
2	Rx Port A, RS-232 (Input to H102)
3	GND (Power, RS-232)
4	CAN high
5	CAN low
6	12 V (Power In, NMEA 2000)
7	CAN ground
8	Alarm
9	PPS
10	No connect, or unterminated drain wire
11	Rx Port C, RS-232 (Input to H102)
12	Tx Port C, RS-232 (Output from H102)

Figure 3-7 shows the H102 I/O location (J60 as marked on the board).

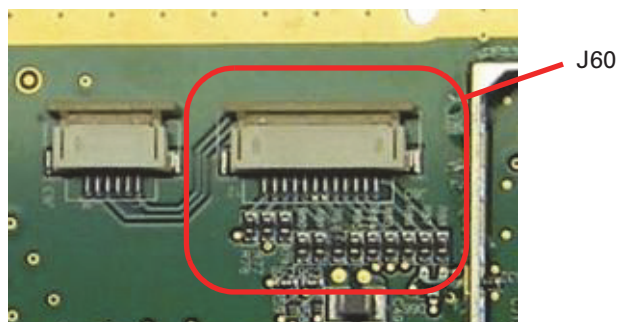


Figure 3-7: H102 I/O locations

Hemisphere GPS strongly recommends using a shielded cable assembly to reduce system noise on the communications lines of the final assembly when designing a cable to connect to the H102. Any data or I/O pins that are not used should be left unterminated.

reacquisition times as well as instances of incorrect heading solutions (see Figure 4-2).

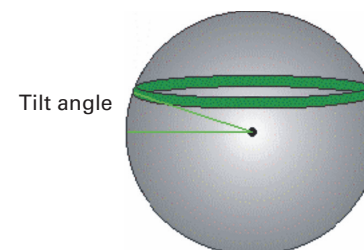


Figure 4-2: H102's tilt aiding

Gyro Aiding

The H102's internal gyro offers several benefits. It reduces the sensor volume for an RTK solution. This shortens reacquisition times when a GPS heading is lost because the satellite signals were blocked. The gyro provides a relative change in angle since the last computed heading, and, when used in conjunction with the tilt sensors, defines the search space as a wedge-shaped location (see Figure 4-3).

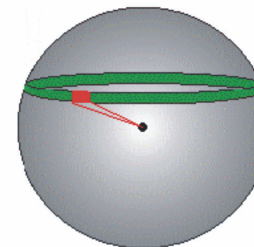


Figure 4-3: H102's gyro aiding

The gyro aiding accurately smoothes the heading output and the rate of turn. It provides an accurate substitute heading for a short period, accurate to within 1° per minute for up to three minutes, in times of GPS loss for either antenna. If the outage lasts longer than three minutes, the gyro will have drifted too far and the H102 begins outputting null fields in the heading output messages. There is no user control over the timeout period of the gyro.

Calibration, which is set at the factory, is required for the gyro to remove latency from the heading solution as well as provide backup heading when GPS is blocked. The receiver will calibrate itself after running for a while but it may be important to follow the manual calibration instructions if you want to guarantee performance quickly after powering up the receiver.

The gyro initializes itself at powerup and during initialization, or you can calibrate it as outlined in the Hemisphere GPS Technical Reference (go to www.hemispheregps.com and click the GPS Reference icon). When the gyro is first initializing, it is important that the dynamics that the gyro experiences during this warmup period are similar to the regular operating dynamics. For example, if you use the H102 on a high speed, maneuverable craft, it is recommended that when gyro aiding in the H102 is first turned on, use it in an environment that has high dynamics for the first five to ten minutes instead of sitting stationary.

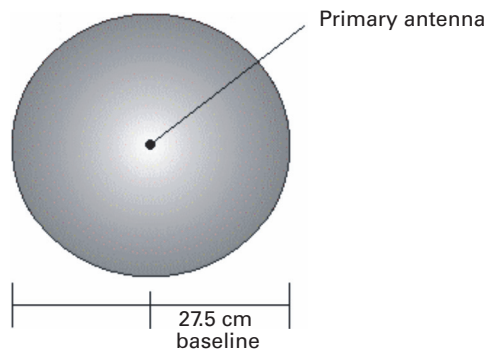


Figure 4-1: Secondary antenna's search volume

Note: The H102 moving base station algorithm only uses GPS to calculate heading. Differential corrections are not used in this calculation and will not affect heading accuracy.

Supplemental Sensors

The H102 has three supplemental sensors (gyro and two tilt sensors) that are integrated into the unit's carrier board. The supplemental sensors are enabled by default. You can enable/disable the gyro and both tilt sensors (you cannot enable/disable each tilt sensor separately).

The sensors act to reduce the RTK search volume, which improves heading startup and reacquisition times. This improves the reliability and accuracy of selecting the correct heading solution by eliminating other possible, erroneous solutions. Table 4-1 provides a sensor operation summary.

Table 4-1: Sensor operation summary

Feature	Normal Operation	Coasting (no GPS)
Heading	GPS	Gyro
Heave	GPS	None
Pitch	GPS	Inertial sensor
Roll	Inertial sensor	Inertial sensor

Refer to the Hemisphere GPS Technical Reference (go to www.hemispheregps.com and click the GPS Reference icon) for the commands and methodology required to recalibrate, query, or change a sensor's status.

Tilt Aiding

The H102's accelerometers (internal tilt sensors) are factory calibrated and enabled by default. This constrains the RTK heading solution beyond the volume associated with just a fixed antenna separation. This is because the H102 knows the approximate inclination of the secondary antenna with respect to the primary antenna. The search space defined by the tilt sensor will be reduced to a horizontal ring on the sphere's surface by reducing the search volume. This considerably decreases startup and

J60 Signals

Table 3-2 describes the signals provided by the J60 connector of the H102.

Table 3-2: J60 signals

Signal	Description
Power	Pin 3 (GND) and Pin 6 (12 V) of the J60 should be used for powering the unit.
I/O communications (port A, port C)	The H102 offers position and heading data via RS-232 level serial ports. The other electronics being used and the serial port level(s) they support will determine which serial port level you can use. The RS-232 interface on Port A must be used to configure output on Port C.
Alarm (non-differential)	Pin 8, non-differential, non-IMO certifiable. The alarm condition occurs when the H102's heading output becomes unusable.
PPS signal (3.3V CMOS)	There is a one pulse per second (PPS) signal on Pin 9 that may be useful for external timing applications or device synchronization. It is a 3.3 V CMOS active high signal with rising edge synchronization, having a 1 ms pulse width.
LED indicators (2)	Located on the edge of the H102 (one for heading, one for power)
CAN High	Pins 3, 4, and 5 offer an isolated Controlled Area Network (CAN) interface (you have to only use CAN connector ports from J60—you cannot mix serial and CAN together). This interface is a full NMEA 2000-certified interface.
CAN Low	
CAN Ground	
CAN Power	Shared with H102 main power supply, Pin 6

Ports

The H102 offers either serial port or NMEA 2000 port functionality.

Serial Ports

The H102 offers position and heading data via two full-duplex (bidirectional) RS-232 serial ports. These ports are also used for firmware upgrades.

Selecting Baud Rates and Message Types

When selecting your baud rate and message types use the following formula to calculate the bits/sec for each message and then sum the results to determine the baud rate for your required data throughput.

Message output rate * Message length (bytes) * bits in byte = Bits/second
(1 character = 1 byte, 8 bits = 1 byte, use 10 bits/byte to account for overhead)

See “Common Commands and Messages” on page 33 for a calculation example. For information on message output rates refer to the Hemisphere GPS Technical Reference (go to www.hemispheregps.com and click the GPS Reference icon).

Configuring the Ports

You may configure Port A or Port C of the GPS receiver to output any combination of data you want. Port A can have a different configuration from Port C in terms of data message output, data rates, and the port baud rate; this allows you to configure the ports independently based upon your needs.

Note: The CAN processor that controls Port C is by default programmed into NMEA 2000 mode. You must configure Port C as a serial port to use the H102 with two serial ports. Port A, which is the main configuration port, is always a serial port. To configure Port C as a serial port refer to Table 3-4 on page 21.

For example, if you want one generalized port and one heading-only port, you can configure the ports as follows:

- Port A to have GPGGA, GPVTG, GPGSV, GPZDA, and GPHDT all output at 1 Hz over a 9600 baud rate
- Port C to have GPHDT and GPROT output at their maximum rate of 20 Hz over a 19200 baud rate

Note: For successful communications use the 8-N-1 protocol and set the baud rate of the H102's serial ports to match that of the devices to which they are connected. Flow control is not supported.

Recommendations for Connecting to Other Devices

When interfacing to other devices, ensure the transmit data output from the H102 is connected to the data input of the other device. The signal grounds must also be connected.

There is likely little reason to connect the receive data input of the H102 to another device unless it is able to send configuration commands to the H102. Since the H102 uses proprietary NMEA 0183 commands for control over its configuration, the vast majority of electronics will not be able to configure its settings unless the other device has a terminal setting where you can manually issue commands.

Differential Operation

The purpose of differential GPS (DGPS) is to remove the effects of selective availability (SA), atmospheric errors, timing errors, and satellite orbit errors, while enhancing system integrity. Autonomous positioning capabilities of the H102 will result in positioning accuracies of 2.5 m 95% of the time. In order to improve positioning quality to better than 1.0 m 95%, the H102 is able to use differential corrections received through the internal SBAS demodulator or externally-supplied RTCM corrections.

Automatic SBAS Tracking

The H102 automatically scans and tracks SBAS signals without the need to tune the receiver. The H102 features two-channel tracking that provides an enhanced ability to maintain a lock on an SBAS satellite when more than one satellite is in view. This redundant tracking approach results in more consistent tracking of an SBAS signal in areas where signal blockage of a satellite is possible.

H102 Overview

The H102 provides accurate and reliable heading and position information at high update rates. To accomplish this task, the H102 uses a high performance GPS receiver and two antennas for GPS signal processing. One antenna is designated as the primary GPS antenna and the other is the secondary GPS antenna. Positions computed by the H102 are referenced to the phase center of the primary GPS antenna. Heading data references the vector formed from the primary GPS antenna phase center to the secondary GPS antenna phase center.

The heading is defined by the orientation from primary to secondary antenna. See Figure 3-1 on page 10 for locations of the primary and secondary antennas.

Fixed Baseline Moving Base Station RTK

The H102's internal GPS receiver uses both the L1 GPS C/A code and carrier phase data to compute the location of the secondary GPS antenna in relation to the primary GPS antenna with a very high sub-centimeter level of precision. The technique of computing the location of the secondary GPS antenna with respect to the primary antenna, when the primary antenna is moving, is often referred to as moving base station Real Time Kinematic (or moving base station RTK).

Generally, RTK technology is very sophisticated and requires a significant number of possible solutions to be analyzed where various combinations of integer numbers of L1 wavelengths to each satellite intersect within a certain search volume. The integer number of wavelengths is often referred to as the “ambiguity” as they are initially ambiguous at the start of the RTK solution.

The H102 restricts the RTK solution. It does this knowing that the secondary GPS antenna is 27.5 cm from the primary GPS antenna. This is called a fixed baseline and it defines the search volume of the secondary antenna as the surface of a sphere with radius 27.5 cm centered on the location of the primary antenna (see Figure 4-1 on page 30).

GPS Overview

For your convenience, both the GPS and SBAS operation of the H102 features automatic operational algorithms. When powered for the first time, the H102 performs a ‘cold start’ that involves acquiring the available GPS satellites in view and the SBAS differential service.

If SBAS is not available in your area, an external source of RTCM SC-104 differential corrections may be used. If you use an external source of correction data, it must support an eight data bit, no parity, one stop bit configuration (8-N-1).

GPS Operation

The GPS receiver is always operating, regardless of the DGPS operation mode. The following sections describe the general operation of the H102’s internal GPS receiver.

Note: Differential source and status have no impact on heading, pitch, or roll. They only have an impact on positioning and heave.

Automatic Tracking

The H102’s internal GPS receiver automatically searches for GPS satellites, acquires the signals, and manages the navigation information required for positioning and tracking.

Receiver Performance

The H102 works by finding four or more GPS satellites in the visible sky. It uses information from these satellites to compute a position within 2.5 m 95%. Since there is some error in the GPS data calculations, the H102 also tracks a differential correction. The H102 uses these corrections to improve its position accuracy to better than 1.0 m 95%.

There are two main aspects of GPS receiver performance:

- Satellite acquisition
- Positioning and heading calculation

When the H102 is properly positioned, the satellites transmit coded information to the antennas on a specific frequency. This allows the receiver to calculate a range to each satellite from both antennas. GPS is essentially a timing system. The ranges are calculated by timing how long it takes for the signal to reach the GPS antenna. The GPS receiver uses a complex algorithm incorporating satellite locations and ranges to each satellite to calculate the geographic location and heading. Reception of any four or more GPS signals allows the receiver to compute three-dimensional coordinates and a valid heading.

⚠WARNING: If you are using a radiator to rebroadcast GPS signals indoors, the H102 may be able to calculate a position solution but it will not be able to compute an accurate heading solution. This is due to the heading algorithms essentially receiving the same measurements at both antennas and is unrelated to the quality or operation of either the H102 or the radiator.

Interfacing to a PC

PCs typically use a DB9-male connector for RS-232 serial port communications. To terminate either port for connection to a PC serial port, connect the wires to a DB9 female connector per Table 3-3 and Figure 3-8.

Table 3-3: Port A and Port C RS-232 interface configuration

J60 Pin	Signal (Port A)	J60 Pin	Signal (Port C)
2	Port A transmit RS-232	11	Port C transmit RS-232
1	Port A receive RS-232	12	Port C receive RS-232
3	Signal ground	3	Signal ground

Figure 3-8 displays the numbering scheme for a DB9 socket connector (female). The associated numbering for the plug connector (male) on a PC computer is a mirror reflection of Figure 3-8.



Figure 3-8: DB9 female socket numbering

NMEA 2000 Port

By default, Port C is configured as a NMEA 2000 port with the default baud rate of 57600.

Table 3-4 lists the commands used to configure Port C back to serial or NMEA 2000 when necessary. You can only send these commands using Port A.

Table 3-4: Commands for changing Port C (must be sent through Port A)

Command	Reply	Description
\$JRELAY,PORTC,\$JSERIALMODE	\$>JSERIALMODE,ENABLED \$>resetting	Switch Port C to serial
\$JRELAY,PORTC,\$JN2KMODE	\$>JN2KMODE,ENABLED \$>resetting	Switch Port C to NMEA 2000

Table 3-5 shows the requested PGNs with the H102 in NMEA 2000 mode.

Table 3-5: Received messages based on a request

PG No. (PGN)	Description	Level	Default Update Rate (msec)	Freq (Hz)
059392	ISO Acknowledgement Used to acknowledge the status of certain requests addressed to a specific ECU.	B	On Request	On Request
059904	ISO Request Request the transmission of a specific PGN, addressed or broadcast.	B	On Request	On Request
060928	ISO Address Claim Used to identify to other ECUs the address claimed by an ECU.	B	On Request	On Request
126996	Product Information NMEA 2000 database version supported, manufacturer's product code, NMEA 2000 certification level, Load Equivalency number, and other product-specific information.	B	On Request	On Request
126464	Receive/Transmit PGNs group function The Transmit / Receive PGN List Group type of function is defined by first field. The message will be a Transmit or Receive PGN List group function.	B	On Request	On Request
129538	GNSS Control Status GNSS common satellite receiver parameter status.	B	On Request	On Request
129545	GNSS RAIM Output Used to provide the output from a GNSS receiver's Receiver Autonomous Integrity Monitoring (RAIM) process. The Integrity field value is based on the parameters set in PGN 129546 GNSS RAIM Settings.	B	On Request	On Request
129546	GNSS RAIM Settings Used to report the control parameters for a GNSS Receiver Autonomous Integrity Monitoring (RAIM) process.	B	On Request	On Request



Chapter 4: Operation

GPS Overview
H102 Overview
Common Commands and Messages


```

$JATT,HRTAU,2.0
$JATT,COGTAU,0.0
$JATT,MSEP,0.275
$JATT,GYROAID,YES
$JATT,TILTAID,YES
$JATT,LEVEL,NO
$JATT,EXACT,NO
$JATT,HIGHMP,NO
$JATT,FLIPBRD,YES
$JATT,HBIAS,0.0
$JATT,NEGTILT,NO
$JATT,NMEAHE,0
$JATT,PBIAS,0.0
$JATT,PTAU,0.5
$JATT,ROLL,NO
$JATT,SPDTAU,0.0

```

```

$JASC,GPGGA,1,PORTA
$JASC,GPGLL,1,PORTA
$JASC,HEHDT,5,PORTA
$JASC,GPRMC,5,PORTA
$JASC,GPROT,5,PORTA
$JASC,GPVTG,1,PORTA
$JASC,GPZDA,1,PORTA
$JASC,GPHPR,1,PORTA

```

Table 3-6 shows the transmitted PGNs with their default update rate with the H102 in NMEA 2000 mode.

Table 3-6: Transmitted messages

PG No. (PGN)	Description	Level	Default Update Rate (msec)	Freq (Hz)
126992	System Time The purpose of this PGN is twofold: To provide a regular transmission of UTC time and date and to provide synchronism for measurement data.	B	1000	1
127250	Machine Heading Heading sensor value with a flag for True or Magnetic. If the sensor value is Magnetic, the deviation field can be used to produce a Magnetic heading, and the variation field can be used to correct the Magnetic heading to produce a True heading.	B	100	10
127251	Rate of Turn Rate of change of the Heading.	B	100	10
127257	Attitude Provides a single transmission that describes the position of a machine relative to both horizontal and vertical planes. This would typically be used for machine stabilization, machine control and onboard platform stabilization.	B	1000	1
127258	Magnetic Variation Message for transmitting variation. The message contains a sequence number to allow synchronization of other messages such as Heading or Course over Ground. The quality of service and age of service are provided to enable recipients to determine an appropriate level of service if multiple transmissions exist.		1000	1
128259	Speed Provides a single transmission that describes the motion of a machine.	B	1000	1
129025	Position, Rapid Update Provides latitude and longitude referenced to WGS84. Being defined as single frame message, as opposed to other PGNs that include latitude and longitude and are defined as fast or multi-packet, this PGN lends itself to being transmitted more frequently without using up excessive bandwidth on the bus for the benefit of receiving equipment that may require rapid position updates.	B	100	10

Table 3-6: Transmitted messages (continued)

PG No. (PGN)	Description	Level	Default Update Rate (msec)	Freq (Hz)
129026	COG & SOG, Rapid Update Single frame PGN that provides Course Over Ground (COG) and Speed Over Ground (SOG).	B	250	4
129027	Position Delta, High Precision Rapid Update Intended for applications where very high precision and very fast update rates are needed for position data. This PGN can provide delta position changes down to 1 mm with a delta time period accurate to 5 msec.	B	100	10
129028	Altitude Delta, High Precision Rapid Update Intended for applications where very high precision and very fast update rates are needed for altitude and course over ground data. This PG can provide delta altitude changes down to 1 millimeter, a change in direction as small as 0.0057°, and with a delta time period accurate to 5 msec.	B	100	10
129029	GNSS Position Data Conveys a comprehensive set of Global Navigation Satellite System (GNSS) parameters, including position information.	B	1000	1
129033	Time & Date Single transmission that provides UTC time, UTC Date, and Local Offset.	B	1000	1
129539	GNSS DOPs Provides a single transmission containing GNSS status and dilution of precision components (DOP) that indicate the contribution of satellite geometry to the overall positioning error. There are three DOP parameters reported: horizontal (HDOP), Vertical (VDOP), and time (TDOP).	B	1000	1
129540	GNSS Sats in View GNSS information on current satellites in view tagged by sequence ID. Information includes PRN, elevation, azimuth, SNR, defines the number of satellites; defines the satellite number and the information.	B	1000	1

Default Parameters

Port C is reserved exclusively for the NMEA 2000 CAN processor and internal communications and is configured by default as a NMEA 2000 port.

To switch Port C to serial:

- Send `$JRELAY, PORTC, $JSERIALMODE`

To switch Port C back to NMEA 2000 mode:

- In version 1.3.0 and earlier, send:
`$JRELAY, PORTC, $JSWITCHN2KMODE14325`
The receiver response is:
`$>JSWITCHN2KMODE14325, ENABLED`
`$>resetting`
- In version 1.3.1 and later, send:
`$JRELAY, PORTC, $JN2KMODE`
The receiver response is:
`$>JN2KMODE, ENABLED`
`$>resetting`

To change the mode of operation to serial pass-through mode:

- Send the following command from Port A:
`$JRELAY, PORTC, $JSERIALMODE`
The receiver response is:
`$>JSERIALMODE, ENABLED`
`$>resetting`

Standard Configuration

The following represents the standard configuration for the H102. For more information on these commands refer to the Hemisphere GPS Technical Reference (go to www.hemispheregps.com and click the GPS Reference icon).

```
$JRELAY, PORTC, $JN2KMODE
$JOFF, PORTA
$JOFF, PORTB
$JOFF, PORTC
```

```
$JBAUD, 19200, PORTA
$JBAUD, 19200, PORTB
$JBAUD, 19200, PORTC
```

```
$JAGE, 2700
$JLIMIT, 10
$JMASK, 5
$JNP, 5
$JWAASPRN, AUTO
$JDIFF, WAAS
$JPOS, 59.0, 18.0
$JSMOOTH, LONG
$JTAU, COG, 0.00
$JTAU, SPEED, 0.00
$JAIR, AUTO
$JALT, NEVER
```

```
$JATT, HTAU, 2.0
```