

magic

GNSS

A product by



IBPL REPORT

Username: johnsmith
Scenario: Example
Start Date: 2009/05/15 (09135)
End Date: 2009/07/27 (09208)
Run Time: 2009/07/28-12:15:50 UTC

All times are GPS Time unless otherwise stated

QUALITY DATA, ALGORITHMS AND PRODUCTS
FOR THE GNSS USER COMMUNITY

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1. CONFIGURATION SUMMARY

1.1. SETTINGS

Station	usn3
Mode	Single-Frequency
Apply Ionospheric Correction	Yes
Apply TGDs	Yes
Apply Tropospheric Correction	Yes
Minimum Elevation Angle	10 deg

Table 1. Settings

2. POSITION ERROR STATISTICS

The position error is the difference between the code-based user position and the precise position (considered as truth). The precise position comes from PPP for user stations and from ITRF (or IGS) for core stations.

	North	East	Up
MEAN	0.334	-0.126	-0.872
STD	0.938	0.703	1.836
RMS	0.995	0.714	2.032
CEP	0.959		

Table 2. Position Error Statistics (meters)

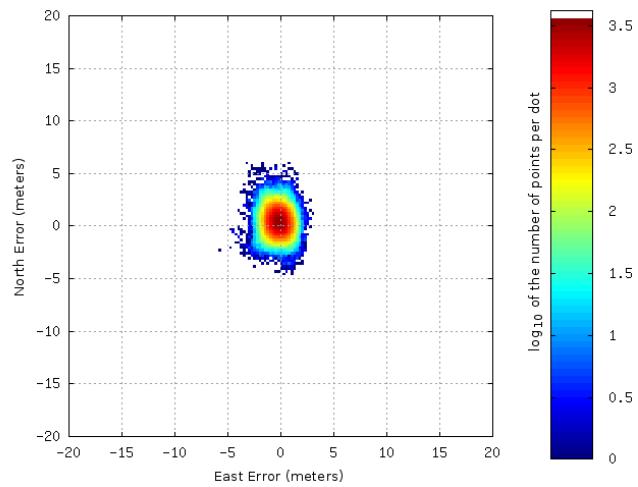
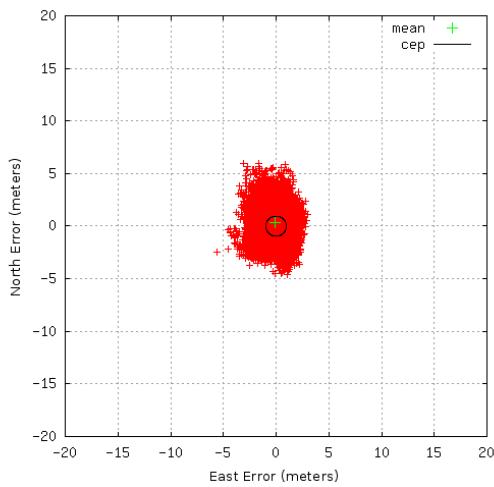


Table 3. Horizontal position errors

3. IBPL ACCUMULATED HISTOGRAMS

The following figures show the accumulated histograms of the horizontal and vertical Protection Levels from IBPL for the GPS-only solution. Seven confidence levels (α) from 10^{-1} to 10^{-7} are considered.

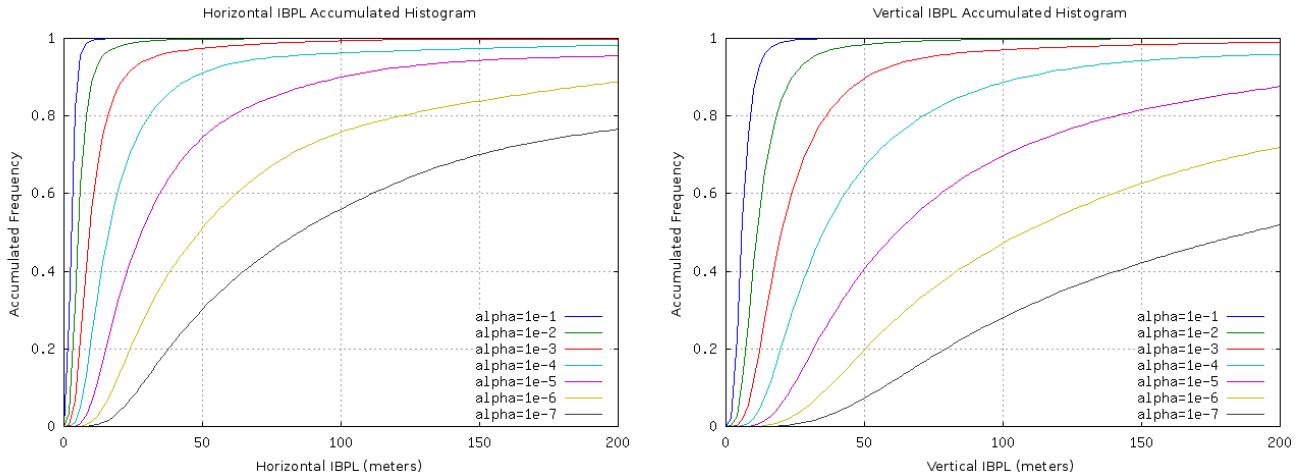


Table 4. IBPL Accumulated Histograms

The following figures show the extrapolation to a GPS+GLONASS/Galileo scenario. The extrapolation only affects the IBPL computation (not the position error) and simply assumes a higher number of satellites in view.

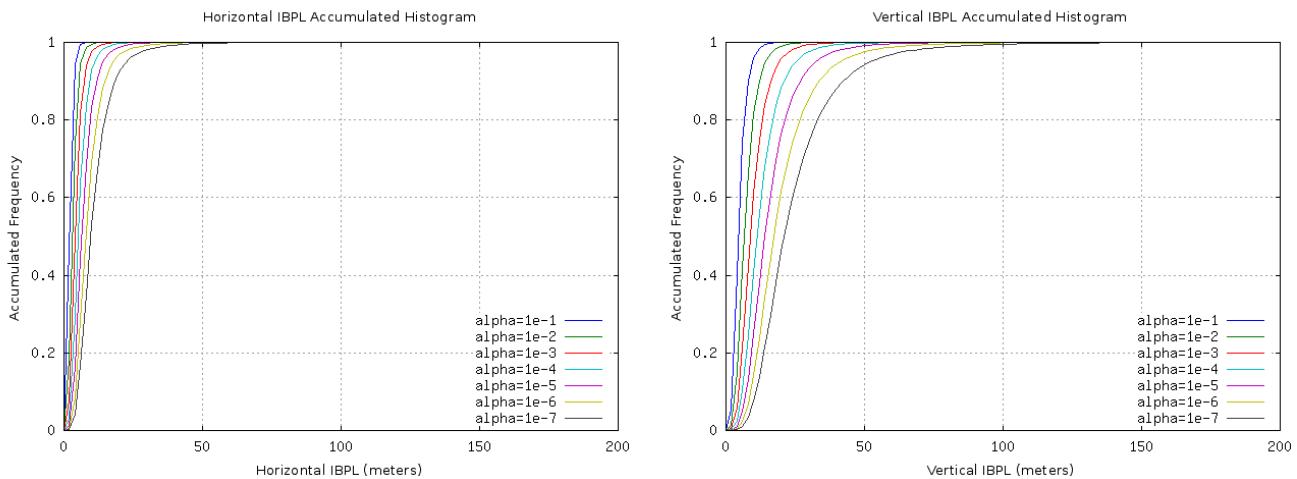
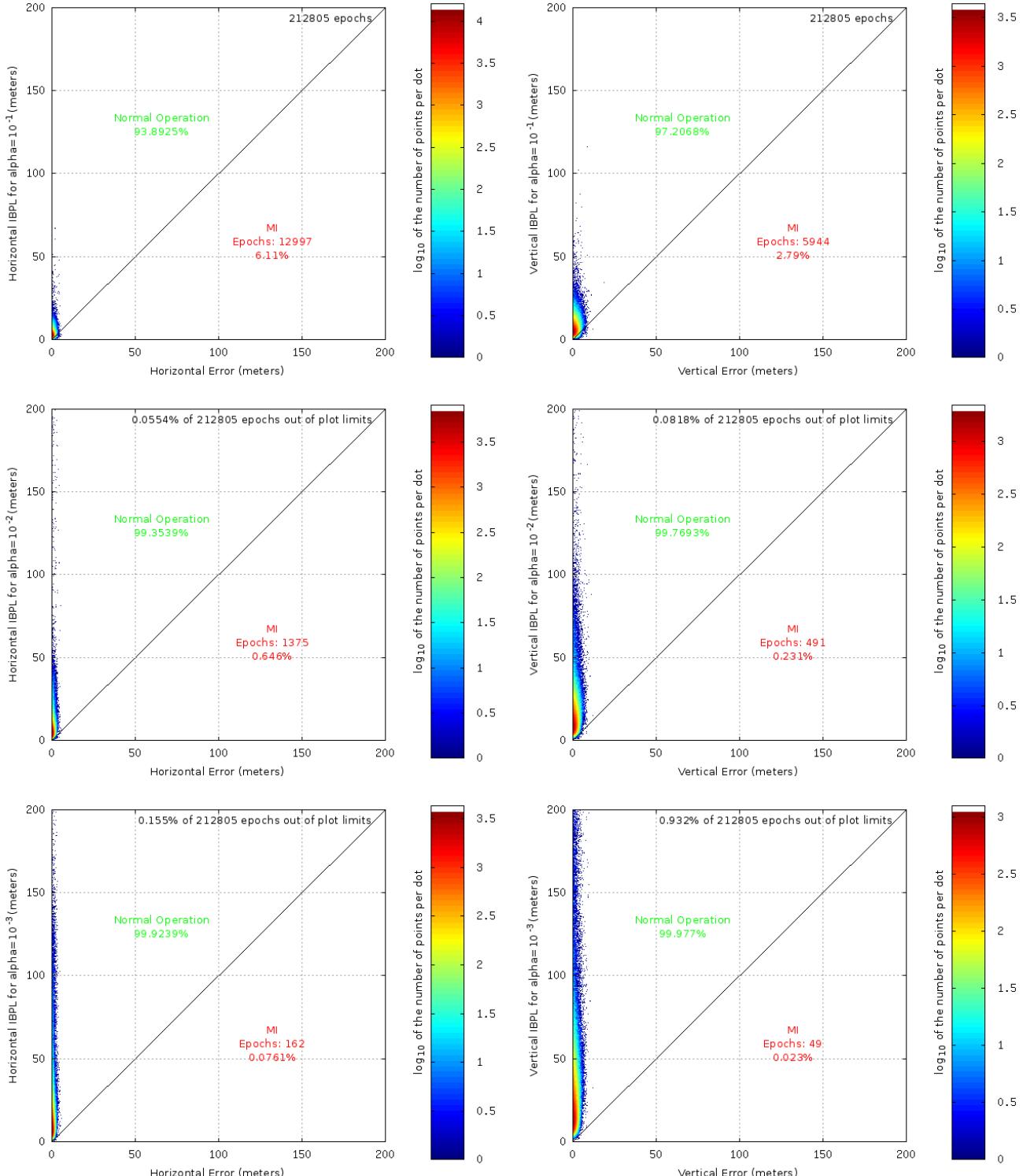
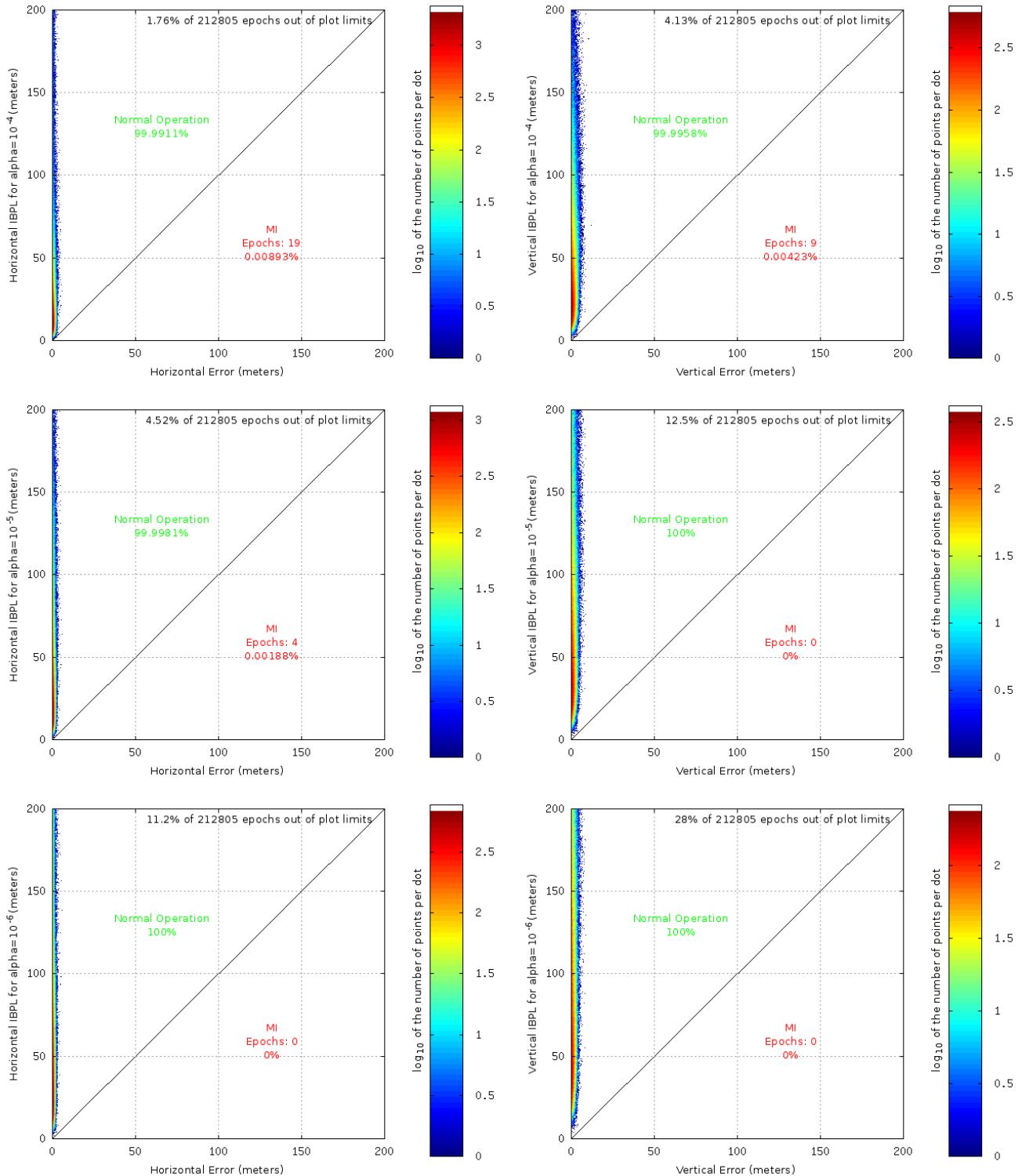


Table 5. Extrapolated IBPL Accumulated Histograms

4. IBPL PERFORMANCES

The following Stanford diagrams represent the Protection Level versus the position error for the different confidence levels.





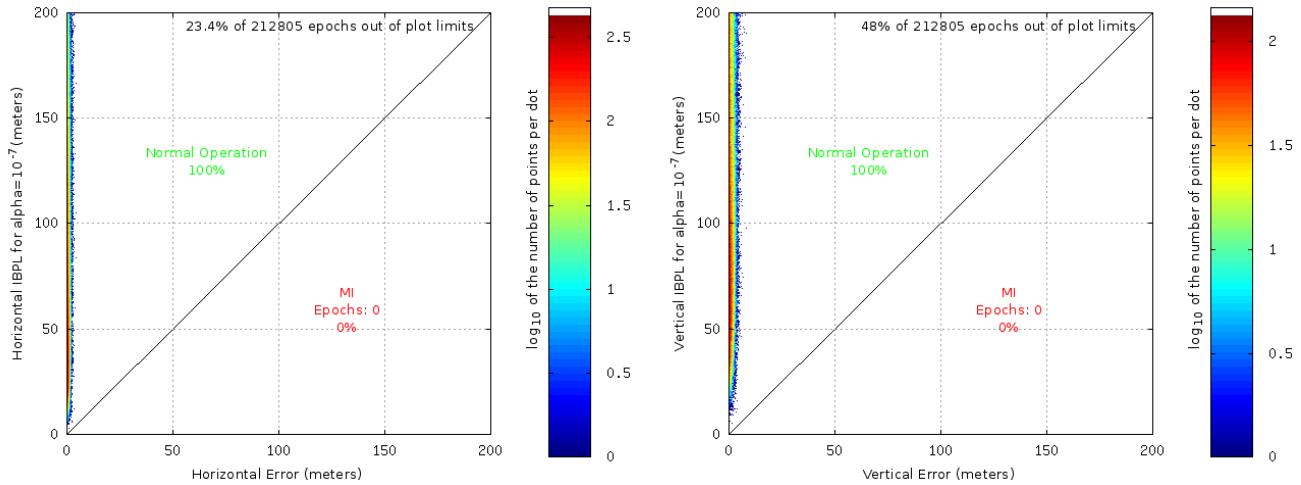


Table 6. IBPL Integrity and Availability

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