

POSLV SPECIFICATIONS

Mobile Geospatial Data Acquisition: Designed for Integration, Built for Performance

When data continuity with position and orientation accuracy is a steadfast requisite for a mobile data application, engineers and geospatial specialists turn to POS LV solutions. For organizations looking to upgrade current GNSS-Only positioning performance or those demanding a proven fully-integrated turnkey position and orientation system, POS LV solutions generate and deliver the robust, reliable, and repeatable results needed to make mobile land-based data acquisition systems profitable and highly productive.

Compact and simple to install or transfer between vehicles, POS LV is quick to learn and has been designed for easy installation with rapid calibration. By conducting operations at normal highway traffic speeds, POS LV accelerates productivity while reducing data collection costs and potential roadside risk to personnel. POS LV may be used with DGPS and RTK corrections, and survey-grade GNSS technology and Distance Measurement Instrument (DMI) integration are standard on all models to ensure superior accuracy performance. POSpac post-processing software is available for further refinement of collected results, lending itself to the production of a far more enhanced and representative data set.

Used by transportation departments, engineering companies, GIS consultants, and mobile mapping system integrators around the world, POS LV provides uninterrupted and precise position and orientation measurements under seemingly impossible GNSS conditions. The POS LV reputation is earned by the continuous high rate (up to 200 Hz) and high accuracy results absolutely necessary for sound mobile survey operations, even despite GNSS signals being blocked or effected (multipath effects) common in urban canyons. Whether used for pavement analysis, asset/infrastructure management, GIS data capture, vehicle dynamics, corridor measurement and visualization, or route monitoring, POS LV helps meet the requirements of any mobile surveying service specialty.

PERFORMANCE SUMMARY - With GNSS*

POS LV	210 PP	210 IARTK	210 DGPS	220 PP	220 IARTK	220 DGPS	420 PP	420 IARTK	420 DGPS	510/520 PP	510/520 IARTK	510/520 DGPS	610 PP	610 IARTK	610 DGPS
X,Y Position (m)	0.020	0.035	0.300	0.020	0.035	0.300	0.020	0.035	0.300	0.020	0.035	0.300	0.020	0.035	0.300
Z Position (m)	0.050	0.050	0.500	0.050	0.050	0.500	0.050	0.050	0.500	0.050	0.050	0.500	0.050	0.050	0.500
Roll and Pitch (°)	0.020	0.020	0.020	0.020	0.020	0.020	0.015	0.015	0.015	0.005	0.008	0.008	0.005	0.005	0.005
True Heading (°)	0.050	0.100	0.200	0.025	0.050	0.050	0.020	0.020	0.020	0.015	0.020	0.020	0.015	0.020	0.020

PERFORMANCE SUMMARY - GNSS Outage, 60 seconds*

POS LV	210 PP	210 IARTK	210 DGPS	220 PP	220 IARTK	220 DGPS	420 PP	420 IARTK	420 DGPS	510/520 PP	510/520 IARTK	510/520 DGPS	610 PP	610 IARTK	610 DGPS
X,Y Position (m)	0.320	1.270	2.510	0.240	0.690	0.880	0.120	0.340	0.450	0.100	0.300	0.420	0.100	0.280	0.410
Z Position (m)	0.130	0.350	0.610	0.130	0.350	0.610	0.100	0.270	0.560	0.070	0.100	0.530	0.070	0.100	0.510
Roll and Pitch (°)	0.060	0.060	0.060	0.060	0.060	0.060	0.020	0.020	0.020	0.005	0.008	0.008	0.005	0.005	0.005
True Heading (°)	0.060	0.100	0.200	0.030	0.070	0.070	0.020	0.030	0.030	0.015	0.020	0.020	0.015	0.020	0.020

* All accuracy values given as RMS. Assumes typical road vehicle dynamics for initialization.

Simply scan the code here or go to www.applanix.com to read more about POSLV.



SYSTEM SPECIFICATIONS

Component	Dimensions (L x W x H) mm	Weight	Power	Temperature	Humidity	Cables
PCS (all models)	167 x 185 x 68	2.4 kg	10 to 34 Vdc power supply	-20 °C to +60 °C	5 to 95% RH**	-
DMI (Applanix)	908 x 115 x 254	2.4 kg	Powered by PCS	-40 °C to +105 °C	-	8 m (standard)
GNSS Antenna*	146 x 146 x 62	0.4 kg	Powered by PCS	-40 °C to +70 °C	-	10 m (standard)
IMU	See below	See below	Powered by PCS	See below	-	8 m (standard)
Aux Power Module (optional)	167 x 185 x 68	2.4 kg	8 to 34 Vdc power supply	-20 °C to +60 °C	5 to 95% RH**	-

INERTIAL MEASUREMENT UNIT (IMU)

Type	Operational Temperature	Models Used In	Maximum Data Rate	Dimensions (L x W x H) mm	Weight
IMU-7 ¹	-54 °C to +71 °C	POSLV 420	200 Hz	158 x 158 x 124	2.5 kg
IMU-17 ¹	-40 °C to +60 °C	POSLV 210/220	100 Hz	158 x 158 x 124	2.5 kg
IMU-21 ^{1***}	-40 °C to +60 °C	POSLV 610	200 Hz	213 x 172 x 172	4.8 kg
IMU-42 ²	-20 °C to +55 °C	POSLV 210/220	200 Hz	158 x 158 x 124	2.6 kg
IMU-46 ²	-20 °C to +55 °C	POSLV 510/520	200 Hz	161 x 120 x 126	2.6 kg
IMU-52 ²	-20 °C to +55 °C	POSLV 420	200 Hz	161 x 120 x 111	1.85 kg
IMU-57 ²	-20 °C to +55 °C	POSLV 610	200 Hz	179 x 126 x 127	2.6 kg

¹ These IMUs require US government approvals for all exports, a Canadian export permit for all destinations outside the US, and may be subject to local export restrictions internationally. Contact your Applanix representative for further information.

² These IMUs are exportable worldwide subject to statutory export declarations, and standard restrictions relating to certain international destinations. Contact your Applanix representative for further information.

GLOBAL POSITIONING SYSTEM OPTIONS

Option	Signals
GPS-17	<p>GPS: L1 C/A, L2C, L2E, L5</p> <p>GALILEO11: L1 BOC, E5A, E5B, E5AltBOC</p> <p>SBAS: Simultaneous L1 C/A and L5</p> <p>BeiDou: B1, B2</p> <p>GLONASS: L1 C/A, L1 P, L2 C/A, L2 P</p> <p>QZSS: L1 C/A, L1 SAIF, L2C, L5</p> <p>L-Band: OmniSTAR VBS, XP, HP and G2</p>

1. GENERAL - SENSORS

IMU: Reliable high performance sensors.
DMI: Rugged construction able to withstand harsh vibration and shock environment, as well as temperature and humidity extremes.

2. ETHERNET INPUT OUTPUT (10/100 Base-T)

Function: Operate POS LV and record data.
Data: Position, attitude, heading, velocity, track and speed, acceleration, status and performance, raw data. All data has time/distance tags.
UDP Port: Display port - low rate (1 Hz data)
TCP/IP Ports: Real-Time Data Port - high rate (1-200 Hz data)
 Logging Data (buffered for data logging)
 Control Port - used by LV-POSView™ (controller software)

3. LOGGING OUTPUT TO REMOVABLE DRIVE

Parameters: Position, attitude, heading, velocity, track and speed, acceleration, status and performance, raw data. All data has time/distance tags.

4. RS232 NMEA OUTPUT

Parameters: Position (\$INGGA), Heading (\$INHDT), Track and Speed (\$INVTG), Statistics (\$INGST), Attitude (\$PASHR), Time and Date (\$INZDA), Events (\$EVT1, \$EVT2)
Rate: 1 - 50 Hz (user selectable)

5. RS232 HIGH RATE DIGITAL OUTPUT

Parameters: Roll, pitch, true heading, latitude, longitude and altitude.
Rate: 1 - 200 Hz (user selectable, IMU dependant)

6. RS232 BASE 1 AND BASE 2 INPUT

Formats: CMR, CMR+, RTCM 2.3

7. OTHER I/O

PPS: One pulse-per-second time sync output. Normally low, active high pulse where the rising edge is the reference.
Event Input: Four input discretes used to mark external events. Discretes are TTL pulses > 1 msec width where rising or falling edge is time tagged and logged. (Maximum rate 300 Hz.)

8. USER SUPPLIED EQUIPMENT

- PC or laptop computer for LV-POSView™ (controller): Pentium 90 processor (minimum), 16 MB RAM, 1 MB free disc space, Ethernet adapter (10/100 base-T, RJ45), Windows 95/98/Me/NT/2000/XP
 - PC for POSPac MMS™ (post-processing): Pentium 4 (32 Bit) at 2 GHz processor, 1GB RAM, 400 MB free disc space 4+ GB for navigation data, USB port, Windows XP Professional
 - 10-34 Vdc power supply, capable of supplying 60 W (peak) power from the host vehicle's electrical system.

* POS LV 210, 510 and 610 Single GNSS, POS LV 220; 420 and 520 Dual GNSS

** Non-Condensing

*** Requires Aux Power Module for supply voltage below 18 Volts

Be sure to ask about our 3 year warranty plan that includes one system upgrade at anytime throughout the warranty period. System upgrade includes PCS (latest version available at time of upgrade request), IMU tophat (as applicable to current system), and standard cables.

Contact support@applanix to find out more.

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