

Local		Remote	
Version	SIK 1.9 on HM-TRP	Version	SIK 1.9 on HM-TRP
FREQ	915	DEVICE_ID	_HM_TRP
RSSI	L/R RSSI: 57/61 L/R noise: 17/32 pkts: 7716 txe=0 rxe=0 stx=0 srx=0 ecc=0/0 temp=-276 dco=0	DEVICE_ID	_HM_TRP
Format	25	Min Freq	915000
Baud	57600	Max Freq	928000
Air Speed	64	# of Channels	50
Net ID	25	Duty Cycle	100
Tx Power	20	LBT Rssi	0
ECC	<input type="checkbox"/>	RTS CTS	<input type="checkbox"/>
Mavlink	RawData	Max Window (ms)	131
Op Resend	<input checked="" type="checkbox"/>	AES Encryption	<input type="checkbox"/>
GPI1_1R/CIN	<input type="checkbox"/>	AES Key	Random
GPI1_1R/COUT	<input type="checkbox"/>		
		Settings for Standard Mavlink Settings for Low Latency	

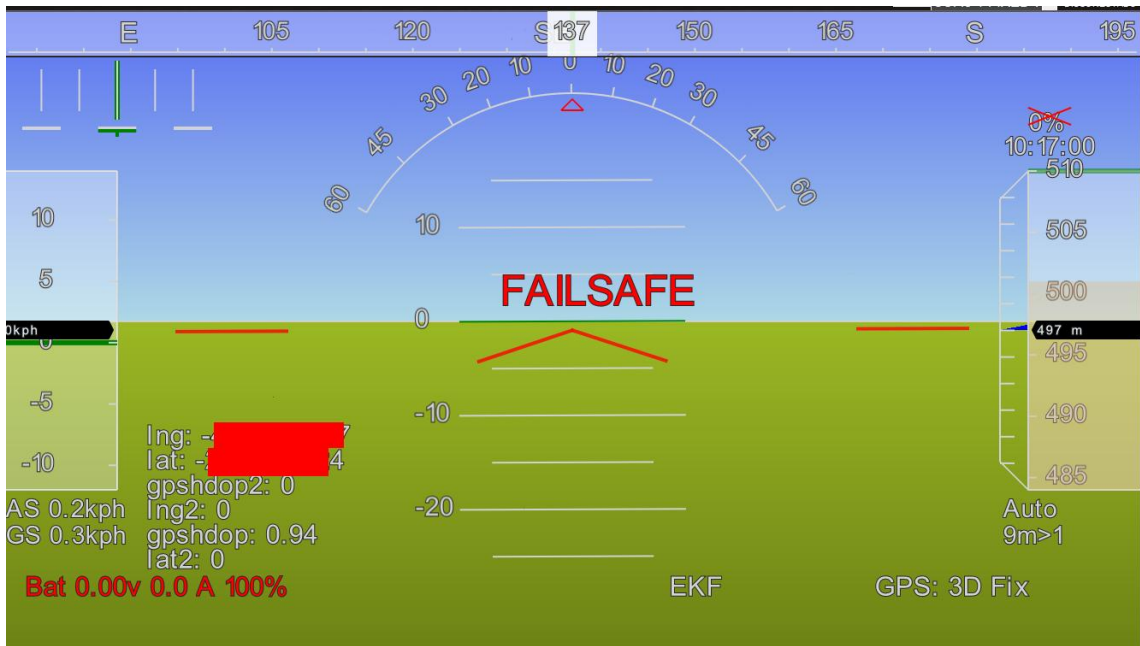
Telemetry setup

Command	Value	Unloads	Options	Desc	Fail
GPS_TYPE2	1		0:None 1:AUTO 2:uBlox 3:MTK 4:MTK19 5:IMB 6:ESP8 7:HL 8:uBlox 9:uBloxCAN 10:SBP 11:GSOF 13:ERB 14:MAV 15:uBlox 16:uBloxCAN 17:uBlox-MovingBaseline-Base 18:uBlox-MovingBaseline- Rover 19:MSP	GPS type of 2nd GPS	<input type="checkbox"/>
SERIAL4_BAUD	38		1:1200 2:2400 4:4800 9:5600 19:11520 28:38400 37:57600 111:1111100 115:115200 220:220400 225:225000 460:460800 500:500000 921:921600 1500:1500000	The baud rate used for Serial4. Most stm32 based boards can support rates of up to 1500. If you setup a rate you cannot support and then can't connect to your board you should load a firmware from a different vehicle type. That will reset all your parameters to defaults.	<input type="checkbox"/>
GPS_AUTO_SWITCH	1		0:Disabled 1:uBlox 2:blend 3:UseSecond	Automatic switchover to GPS reporting best lock	<input type="checkbox"/>
GPS_BLEND_MASK	5			Determines which of the accuracy measures Horizontal position, Vertical Position and Speed are used to calculate the weighting on each GPS receiver when soft switching has been selected by setting GPS_AUTO_SWITCH to 3(Blend)	<input type="checkbox"/>
GPS_INJECT_TO	1		0:send to first GPS 1:send to 2nd GPS 127:send to all	The GGS can send raw serial packets to inject data to multiple GPSes.	<input type="checkbox"/>

Config setup

The screenshot shows the Mavlink configuration interface. At the top, there's a 'TCP Client' section with a 'Stop' button and 'L2K Status' showing 'Input data rate: 285 bps' and 'Output data rate: 285 bps sent'. Below that, there's a 'Novia Navigen RTCM' section with a 'Send GGA?' checkbox. The 'RTCM' status is shown as 'RTCM Base: 478.855218'. At the bottom, there's a data stream visualization showing a series of green bars representing data packets, with a red line indicating a threshold.

Reach RS+ (base) connected.



Only GPS1 working, GPS2 (Reach M+) not.

M+ v2.24.0

Correction input

Base correction OFF ON

Serial NTRIP TCP LoRa BT

Device
 UART

Baud rate
 38400

i Correction input format is RTCM3

Send NMEA GGA messages to the corrections provider (required for VRS)

• Connected to /dev/ttyMFD2

M+ v2.24.0

Position output

Output 1 OFF ON

Serial TCP BT

Device
 UART

Baud rate
 38400

Format
 ERB

• Connected to /dev/ttyMFD2

Output 2 OFF ON

Serial TCP BT

• No info

M+ v2.24.0

Base mode

Corrections output OFF ON

Serial NTRIP TCP LoRa BT

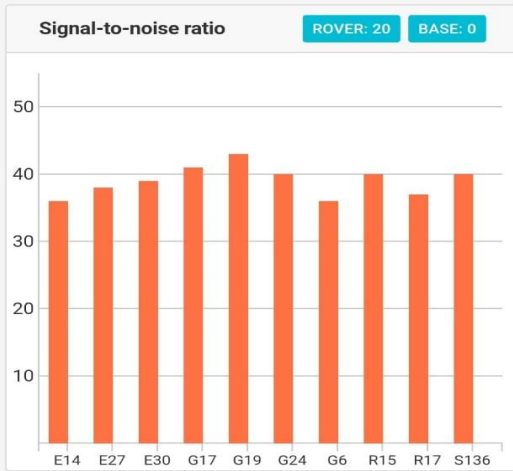
Base coordinates ↻ ↕

Coordinates input mode
 Average single

Coordinate accumulation time
 2 min 30 min

•

Status



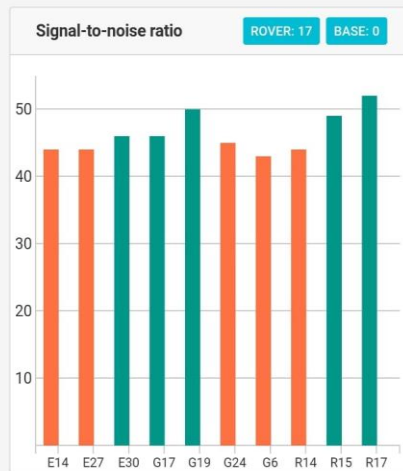
RTK parameters

0.0 sec	0.0	0.00 m
● age of differential	● AR validation ratio	● baseline

Positioning mode

Solution status

Status



RTK parameters

0.0 sec	0.0	0.00 m
● age of differential	● AR validation ratio	● baseline

Positioning mode

Solution status

Correction input

Base correction OFF ON

- Serial
- NTRIP
- TCP
- LoRa
- BT

-

Position output

Output 1 OFF ON

- Serial
- TCP
- BT

Device

UART

Baud rate

38400

Format

ERB

• Connected to /dev/ttyMFD2

Output 2 OFF ON

- Serial
- TCP
- BT

• No info

Base mode

Corrections output

OFF ON

Serial NTRIP **TCP** LoRa BT

Role

Server

Address

localhost

Port

9000

Corrections output format is RTCM3

Base coordinates



Coordinates input mode

Average single

