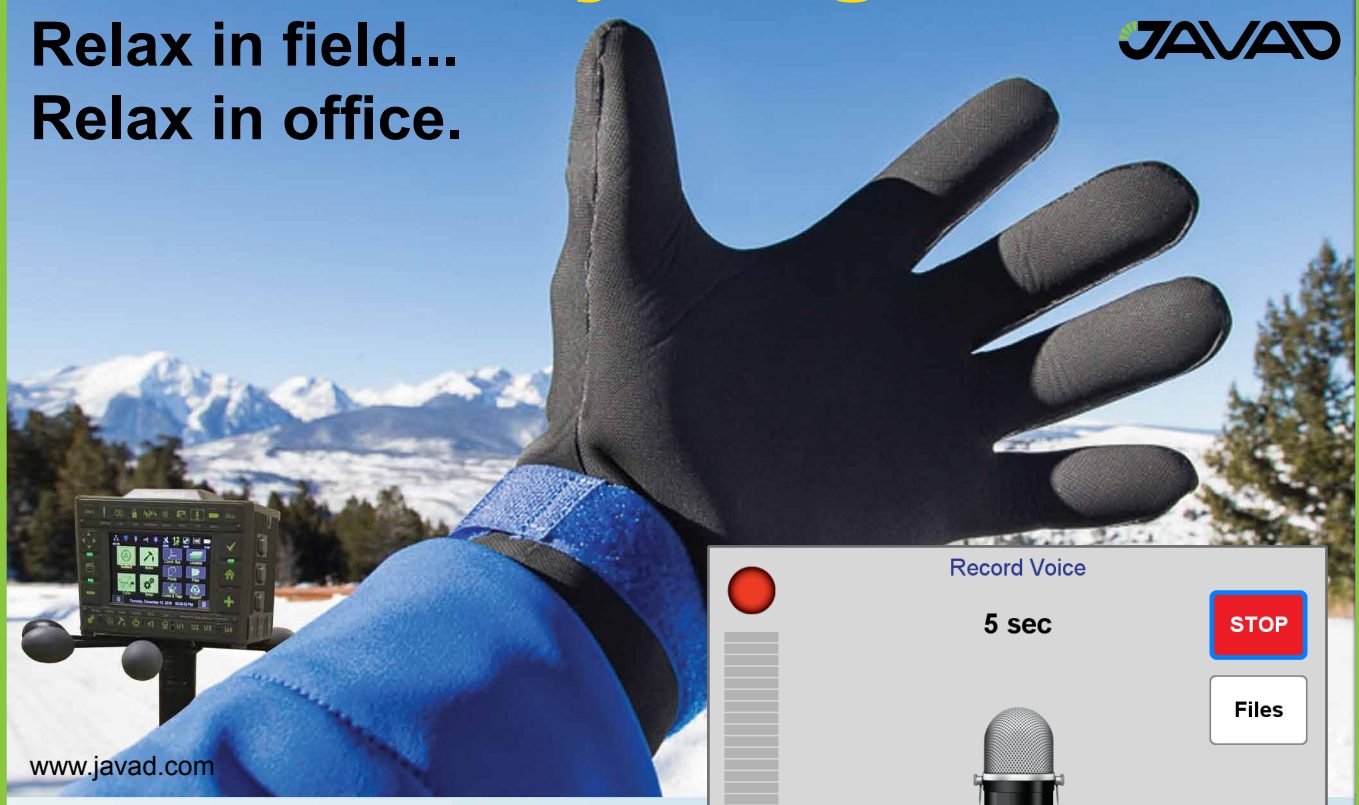
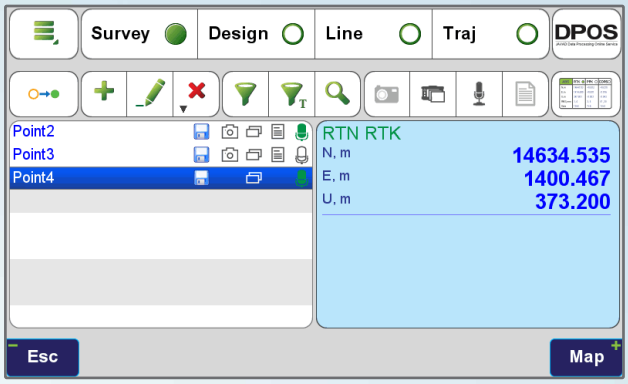
Don’t take your gloves off!

Relax in field...
Relax in office.



1. Start by proximity sensor – stops automatically when all OK
2. Talk all info in microphone.
3. Takes photos and screen shots automatically or manually
4. TRIUMPH-LS converts to text automatically and created HTML and PDF reports.

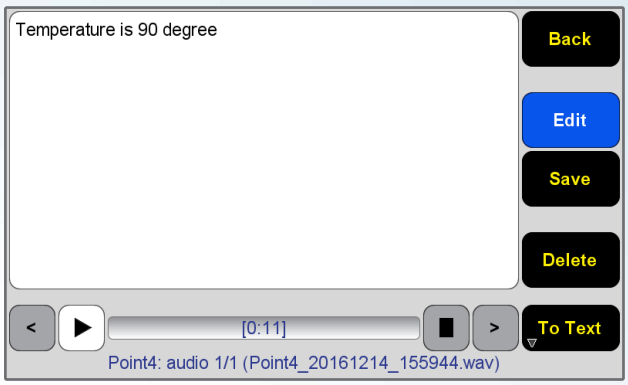


Icons description:

Raw GNSS data
Photo
Screenshots
Notes
Audio file
Audio file converted to text

to Text – converts voice to text. Long push converts all voice files attached to this point

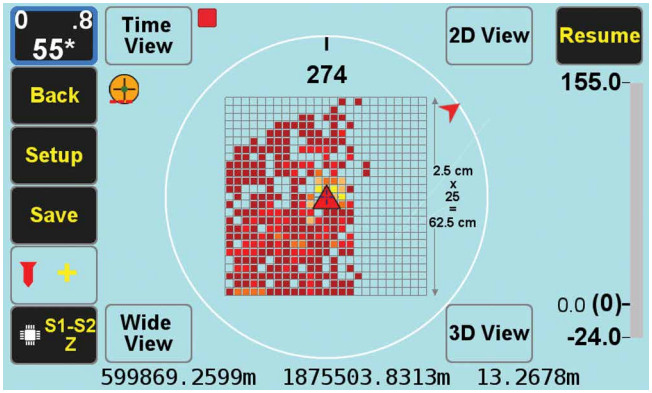
Edit – edit text after conversion and Save. Long push on these icons goes directly to screens to attach more.



Front

J-Tip

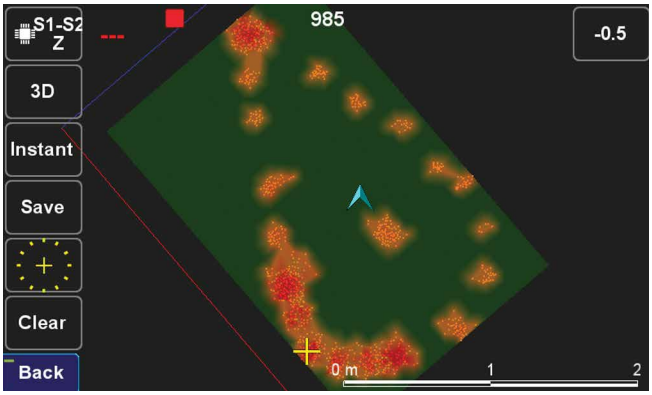
TRIUMPH-LS tags coordinates with magnetic values, It also guides you to top of the item to survey it.

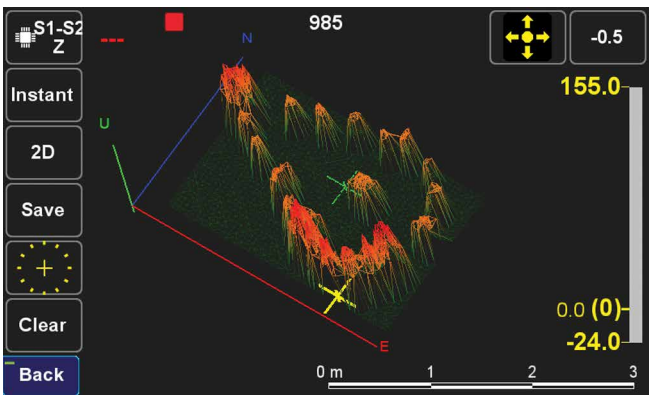


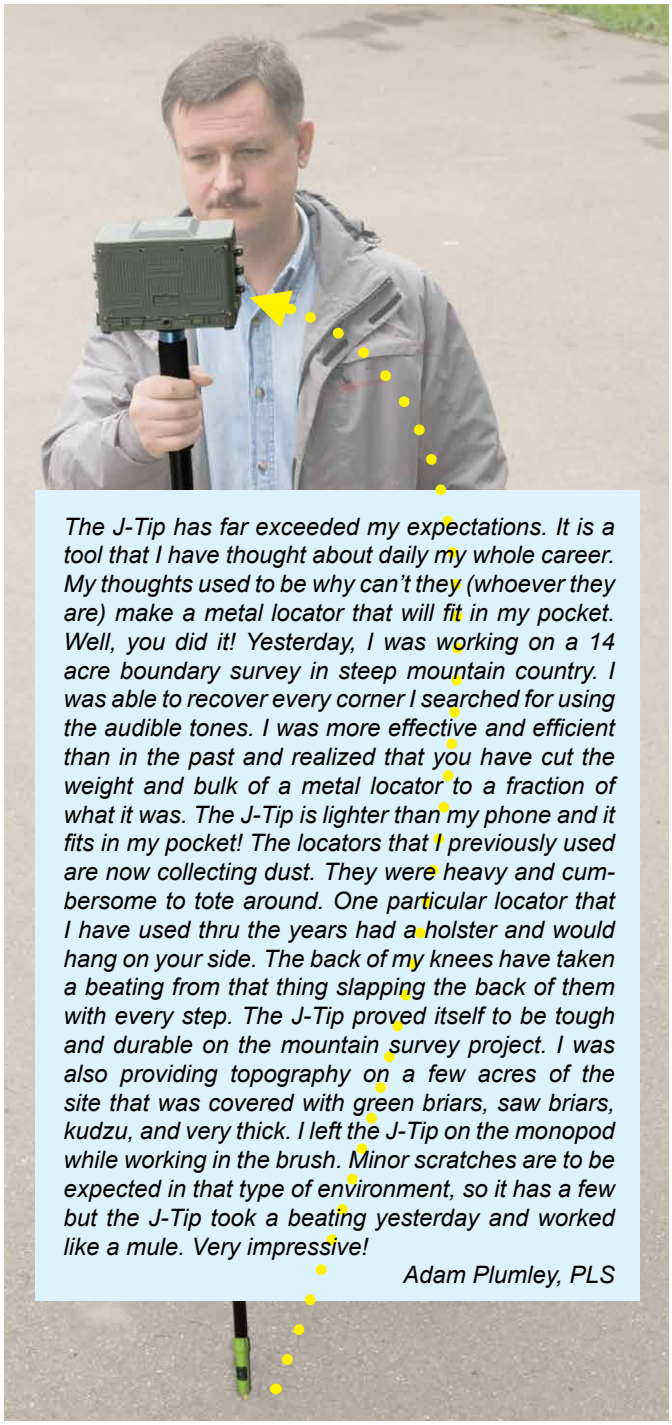
The Mag View focuses only on the mag object with the highest mag value.

The audio and graphical bar on the right side show the magnitude of the magnetic object.

In “Setup” you can select the cell size and the size of the field you want to scan.







The J-Tip has far exceeded my expectations. It is a tool that I have thought about daily my whole career. My thoughts used to be why can't they (whoever they are) make a metal locator that will fit in my pocket. Well, you did it! Yesterday, I was working on a 14 acre boundary survey in steep mountain country. I was able to recover every corner I searched for using the audible tones. I was more effective and efficient than in the past and realized that you have cut the weight and bulk of a metal locator to a fraction of what it was. The J-Tip is lighter than my phone and it fits in my pocket! The locators that I previously used are now collecting dust. They were heavy and cumbersome to tote around. One particular locator that I have used thru the years had a holster and would hang on your side. The back of my knees have taken a beating from that thing slapping the back of them with every step. The J-Tip proved itself to be tough and durable on the mountain survey project. I was also providing topography on a few acres of the site that was covered with green briars, saw briars, kudzu, and very thick. I left the J-Tip on the monopod while working in the brush. Minor scratches are to be expected in that type of environment, so it has a few but the J-Tip took a beating yesterday and worked like a mule. Very impressive!

Adam Plumley, PLS

2D and 3D views of the field show the magnetic objects that have been scanned.

Zooming the 2D and 3D screens can show the shape of the magnetic objects under the ground.

For many sophisticated features of the J-Tip see its Users Manual in www.javad.com

Concepts Behind RTK Verification

Fundamental in the determination of GNSS solutions is calculating the correct number of full wavelengths (so-called ***fixing ambiguities***) in order to figure out the distances from the satellites to the receiver. In doing Real Time Kinematic (RTK) surveying, we need it fast and we need it to be correct.

Multipath, the reflections of GNSS signals from ground and nearby objects and structures create their own indirect measurements from the satellites to the GNSS receiver. It's as if your measuring tape is bent around an obstacle such as a tree instead of a free and clear line of sight between two points. No calculator is going to improve this result.

TRIUMPH-LS has sophisticated hardware to distinguish between the direct and indirect signals and remove most of the indirect signals. It also reports the amount of indirect signal that has been removed. The worst case is when the receiver doesn't see the direct signal at all; e.g., the satellite is behind a building, but it's still receiving the signal reflected off of the nearby structure. It is the task of the RTK engines to isolate such indirect signals and then exclude them from the calculations.

If too many of the signals are affected by severe multipath or indirect signals, no solution may be found. Remember, indirect signals are analogous to the bent measuring tape! When you're preforming RTK surveying, observe your environment and come to recognize that the structures around you are like mirrors for GNSS signals.

The other aspect impacting the veracity of a fixed solution is when there are weak GNSS signals. Frequently, weak signals are due to their penetration directly through tree canopy.

While the **TRIUMPH-LS** can't move the obstacles that are creating multipath out of the way, its sophisticated hardware has advanced multipath reduction sub-system, its tracking software is designed to handle even the weakest signals, and its **J-Field** software provides reliable RTK solutions like no other system with its **Automatic RTK Verification System** (patent pending). J-Filed also has ample tools to demonstrate the reliability of the solution or warn against questionable results. You can readily see that without such tools other systems can provide you wrong and misleading solutions.

J-Field uses six RTK engines (Figure 1) running in parallel plus a support engine to monitor and aid the six engines. Each engine uses a different criteria and mathematical method tailored to resolve ambiguities in different conditions. These six parallel engines not only verify robust solutions but also maximize the possibility of providing solutions in all conditions.

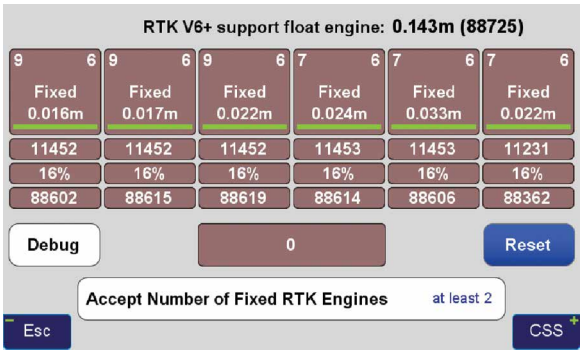


Figure 1 *V6+ six RTK Engines*

User Defined Verification Tools

J-Field provides the option for you to specify the **Minimum Number of Fixed RTK Engines** in verifying solutions **N** times before a position is automatically accepted where **N** is a user defined value.

J-Field employs two metrics to evaluate the performance of its RTK system of six engines: **1) Confidence Counter, and 2) Consistency Counter.** (Figure 2)

Confidence Counter

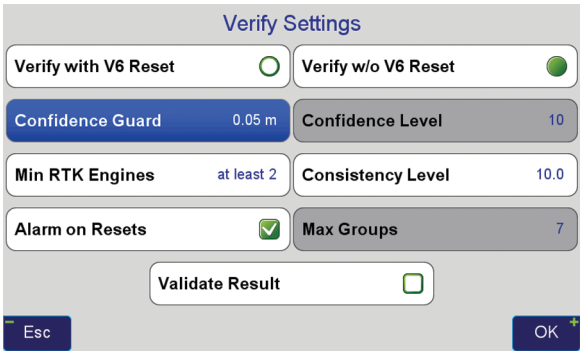


Figure 2 *Verify Settings*

This metric is incremented each time an engine is reset, ambiguities are recalculated, and the solution is in agreement with the previous ones (as defined by the **Confidence Guard (CG)**, default value 5 cm) is achieved. The Confidence Counter increments by 1, 1.25, 1.5, 1.75, 2.0, and 2.5 depending on the number of reset engines that fix in that epoch.

Consistency Counter

The Consistency Counter is incremented each time a solution is in agreement with the previous ones (as defined by the Confidence Guard) irrespective of engines being reset or not. The Consistency Counter is incremented by 0.0, 0.1, 0.25, 0.5, 1.0 and 1.5 depending on the number of fixed engines used in that epoch. Note that one fixed engine gets no credit and 6 fixed engines gets a **Consistency Credit** of 1.5.

Using these Confidence and Consistency verification tools, J-Field has two options to achieve reliable RTK solutions: **1) Verify With Automatic RTK Engines Resets** and **2) Verify Without Automatic RTK Engines Resets.**

Verify with Automatic RTK Engines Resets

This method has two steps: **1) Confidence Building** and **2) Smoothing and verifying**.

• **Step One.** In Step One, fixed engines are reset and solutions are collected into groups. Each group contains all the epochs located within a specified radius (the CG value) from its center and new groups are created as necessary so that all epochs fall into at least one group. Each group has its own Epoch Counter, Confidence Level and Elapsed Time. A point may fall into more than one group. The groups are sorted from best to last by the sum of their Time and Confidence with the current best group being shown within [ ] and others within ( ). Step One continues until a group reaches the Confidence Level. (Figure 3)

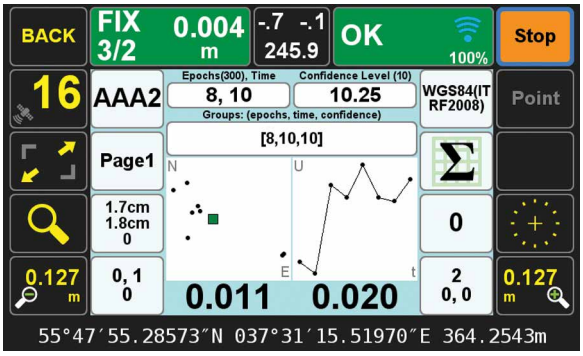


Figure 3 *End of Step one*

• **Step Two.** During Step Two the engines are not reset and solutions which are located inside the CG of the selected Group are added to that Group for the remaining number of epochs that user has requested (Epoch Number, EN) in the How to Stop screen. Epochs which are outside the CG of the selected Group will be stored in a new (or previously created) group; the RTK engines are reset if the epoch falls outside a sphere with a radius twice that of the CG and the process will then revert back to Step One and the Confidence Level of the current group will be reset to 0.

If the number of epochs falling outside of the current group (but less than 2X outside it) reaches 33% of epochs collected so far, the process will revert back to Step One. Previously created groups will remain intact and once an existing or previously created group meets the Step One criteria, it will pass to Step Two. (Figure 4)

In both steps the Consistency Counter is also incremented as mentioned earlier.

You can manually reset all RTK engines via the

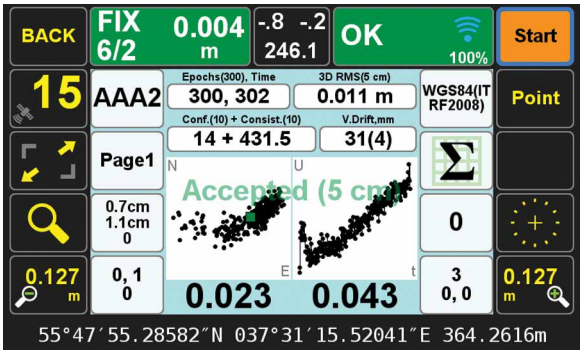


Figure 4 *End of Step 2*

V6-RTK engines screen (Figure 1), or assign this reset function to any one of the U1 to U4 hardware buttons in front of the TRIUMPH-LS for easy access.

Verify without Automatic RTK Engines Resets:

In this method we don't force the RTK engines to reset but rely mostly on the Consistency Counter. There will be only one group as selected by the first epoch. Solutions that are not within the Guard band of the current average will be thrown out. If more than 30% of solutions are thrown out, the process will restart.

The horizontal and vertical graphs presented in both approaches also help the surveyor to evaluate the final solution. The linear drift of the vertical solution and its drift RMS are also shown above the vertical graph. A high linear drift (more than few centimeters) reveals severe multipath or, in rare cases, a wrong ambiguity fix. Pay close attention to the vertical drift and the horizontal and vertical scatter plots of epochs. Consider the scatter plots as doctors examine X-rays to determine anomalies.

The desired **Confidence Level** and **Consistency Level** are user selectable. Default values are 10. These parameters along with the desired number of epochs must be reached before a solution is provided.

In either case there is also a **Validate** option which, when selected, will reset all engines at the end of the collection and continues with 10 more epochs to validate if the solution is within the desired boundary of the Confidence Guard. (Figure 2) Minimum number of engines for the Validation Phase is user selectable.

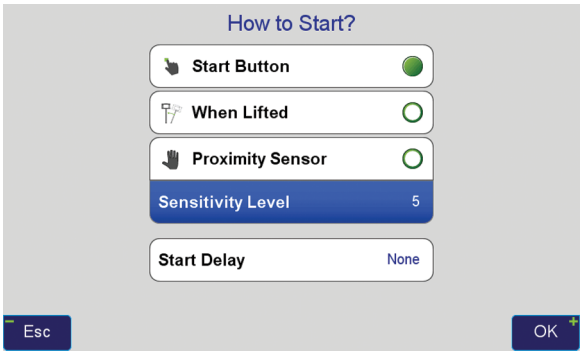


Figure 5 *How to Start*

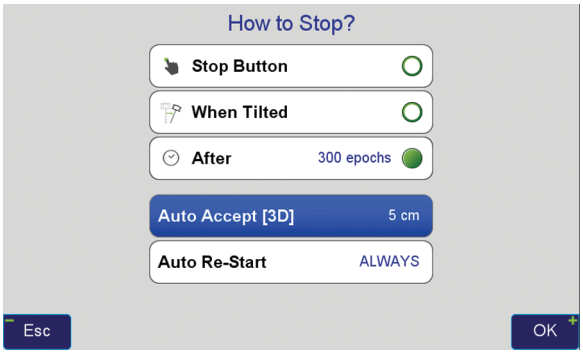


Figure 6 *How to Stop*

In either case, if Auto-Accept is activated, the position will be automatically accepted if the RMS of the final solution is less than what user has selected in the Auto-Accept screen. (Figure 6)

You can also use **Auto-Restart** if you want to monitor structures or test the RTK system unattended. (Figure 6)

Screen Shots of Action Screen

Action Screen shows detailed information about each point collected. Screen shots can automatically be attached to each point and saved at the end of each collection (Figure 7). In **Verify with Automatic RTK Engines Resets** screen shots at the end of both Step One and Step Two are saved (Figures 3 and 4). In Action screen there are 8 white boxes that selected items can be viewed on them.

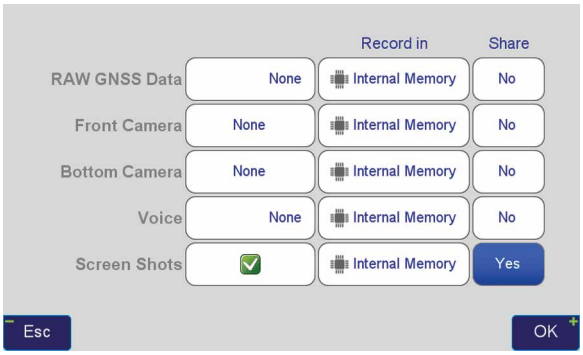


Figure 7 *What to record screen*

Review Screen

View cluster of all points. Select the desired point to see its point cluster (Figure 8). Click the icons to see additional details about that point (Figure 9) including the distance and direction to the current point (Figure 10).

The effects of multipath, ionosphere, orbit, and other sources of problems somewhat exponentially increase as the baseline length increases. In a VRS/RTN scheme your **actual** baseline length is the actual distance to the nearest base station. The **virtual** base station that is mathematically created is not the actual length. We strongly recommend using your own base station near your job site in a Verified-Base RTK (VB-RTK) scheme.

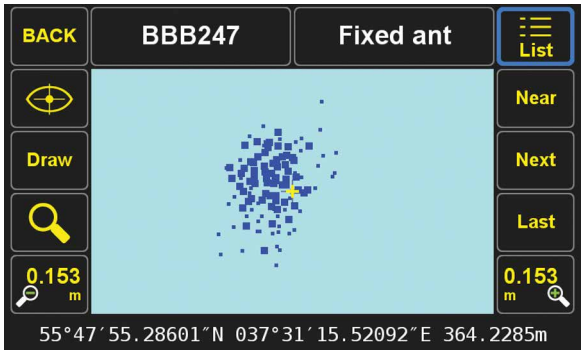


Figure 8 *Review screen shows cluster of 386 points*

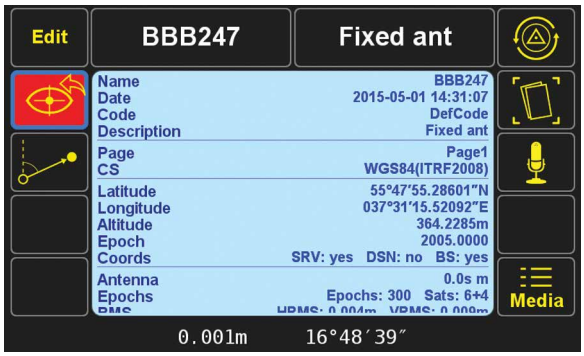


Figure 9 *Detailed information on selected point (scroll to see all information)*

Figure 10 *Distance and direction from the current point to the selected point*

In addition to providing you with the most reliable RTK solutions (especially true in remote areas where cell coverage is hit or miss), using your own base receiver allows you to easily tie your solutions to well-established IGS/NGS spatial reference systems through Javad's exclusive Data Processing Online Service (DPOS) and J-Field's user-friendly Base/Rover Setup. Note that post-processed results returned to the TRIUMPH-LS using DPOS are dependent on the availability of orbital data from NGS and may require several hours. For further reading about DPOS, its integration into J-Field and the streamlined approach developed by Javad for setting up the base and rover, please check out Shawn Billings' excellent article on VB-RTK on our

website. Point your browser to: *http://www.javad.com/jgnss/javad/news/pr20150219.html*

Alternatively, if you don't have access to IGS-type stations to use DPOS, you can select an open area near your job site and use TRIUMPH-LS to obtain its position via RTN networks for about 5 minutes. You may repeat a couple of times for assurance. Then transfer this position to the TRIUMPH-1 or TRIUMPH-2 to use as the base station near your job site. The Base-Rover setup screen in the TRIUMPH-LS makes this job very easy.

Instantaneous Multipath charts

TRIUMPH-LS removes most of the multipath instantly on every epoch. Click on the Satellite icon to see the Signal Strength of satellites and then click the "+" key to see the multipath charts.

Figure 11 shows the amount of code phase multipath that TRIUMPH-LS has removed; relative to a fixed level. That is why negative numbers are in this figure. Units are in centimeter. Noting the signs in this figure, the amount of multipath in some satellites is in excess of 5.6 meters.

Figure 12 shows the amount of carrier phase multipath that TRIUMPH-LS has removed relative to a fixed level. Units are in millimeter. Noting the signs in this figure, the amount of multipath in some satellites is in excess of 4 centimeters.

SAT	EL	L1	P1	P2	L2C	L5	SAT	EL	L1	P1	P2	L2C	L5
GPS2	29↑	273	281	-76	--	--	BDU11	75↑	362	--	--	--	305
GPS6	44↑	55	201	-60	-5	189	BDU12	36↓	288	--	--	--	200
GPS12	70↑	183	190	-90	-94	--	GPS3	10	--	--	--	--	--
GPS14	25˜	281	317	-97	--	--	GPS29	3	--	--	--	--	--
GPS17	23↓	332	364	-74	6	--	GPS32	3	--	--	--	--	--
GPS24	53↓	117	566	67	-64	124	GLN7	3	--	--	--	--	--
GPS25	30↑	243	218	-42	-50	-34	GLN19	12	--	--	--	--	--
GLN1	10↑	305	229	-126	-404	--							
GLN8	16↓	26	87	-484	-617	--							
GLN9	32↑	359	301	-246	55	--							
GLN15	31↓	276	203	-93	-2	--							
GLN16	84↑	235	309	-133	-109	--							
GLN17	39↓	52	-84	-156	-52	--							
GLN18	69↑	190	168	-177	-184	--							
GAL12	68˜	680	-121	246	--	32							
SB127	25˜	469	--	--	--	319							
SB128	15˜	206	--	--	--	322							
QZ193	13↑	550	513	--	56	55							
BDU2	16˜	299	--	--	--	275							
BDU5	25˜	269	--	--	--	230							
BDU8	25↓	145	--	--	--	143							

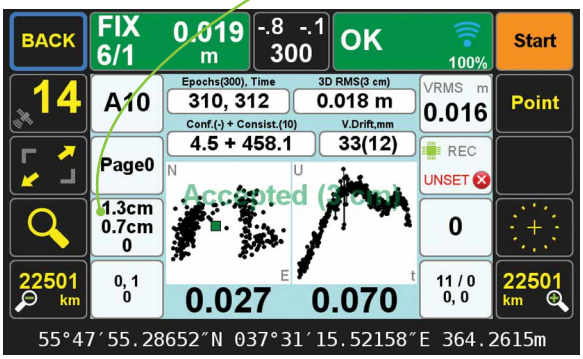
Figure 11 *Code Phase multipath removed (cm)*

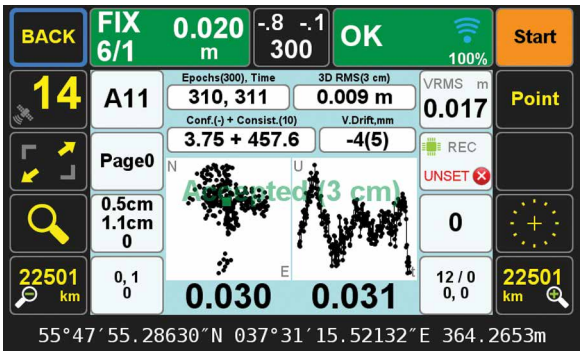
SAT	EL	AZ	L1	P1	P2	L2C	L5	SAT	EL	AZ	L1	P1	P2	L2C	L5
GPS2	29↑	154	7	7	2	--	--	BDU11	75↑	158	-6	--	--	--	-5
GPS6	44↑	98	11	9	2	2	-13	BDU12	36↓	60	-6	--	--	--	-14
GPS12	70↑	282	7	8	-2	-2	--	GPS3	10	26	--	--	--	--	--
GPS14	25˜	302	5	8	-4	--	--	GPS29	3	229	--	--	--	--	--
GPS17	23↓	58	6	9	-6	-2	--	GPS32	3	346	--	--	--	--	--
GPS24	53↓	196	1	4	13	1	-12	GLN7	3	297	--	--	--	--	--
GPS25	30↑	282	4	8	7	1	-32	GLN19	12	210	--	--	--	--	--
GLN1	10↑	34	1	4	-15	-23	--								
GLN8	16↓	344	12	15	17	25	--								
GLN9	32↑	316	0	2	-3	-6	--								
GLN15	31↓	142	5	5	0	1	--								
GLN16	84↑	266	2	2	-11	-18	--								
GLN17	39↓	44	-1	-4	-12	-10	--								
GLN18	69↑	188	-1	3	-1	-6	--								
GAL12	68˜	108	0	-26	0	--	-14								
SB127	25˜	160	7	--	--	--	-4								
SB128	15˜	130	9	--	--	--	-11								
QZ193	13↑	68	-3	-1	--	1	-19								
BDU2	16˜	132	-7	--	--	--	-17								
BDU5	25˜	154	-4	--	--	--	-7								
BDU8	25↓	54	-10	--	--	--	-20								

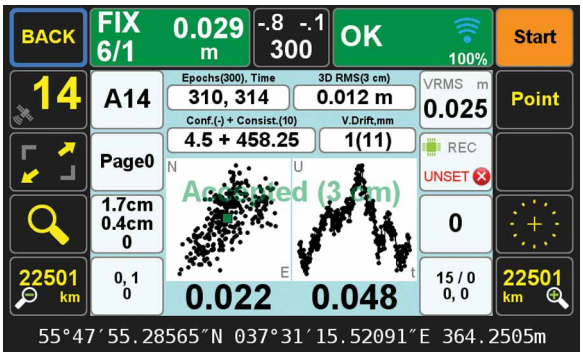
Figure 12 *Carrier Phase multipath remove (mm)*

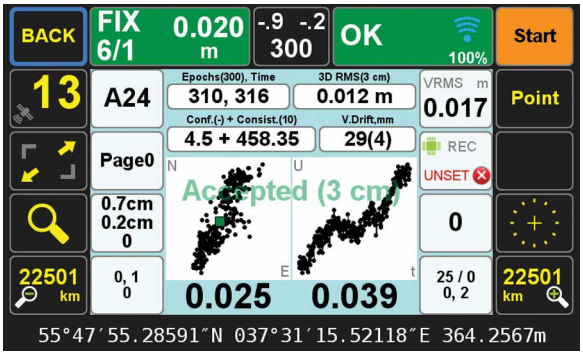
Multipath Showcase

Graphs in the following examples show multipath effects in a 13.8 km baseline where about 1/3 of the rover sky was blocked by a tall building. This box shows horizontal (top) and vertical (bottom) offsets from the actual coordinates of the point (earlier surveyed for test).









Javad Ashjaee, Ph.D.

TRIUMPH-LS
Rugged, Tough, Versatile

Built on a tough magnesium alloy chassis, all connectors, SIM cards, Micro-SD cards are protected against the harshest environment.

You can collapse the pole and take the unit next to you in your car seat.

9 buttons provide **direct access to all functions**. Six keys are user programmable.

The **built in GNSS full tracking antenna** has a large ground plane and the best centering and rotational performance on the market.

High resolution 800x480 pixels sunlight readable color display

Built in UHF, FH Spread Spectrum, WiFi, Bluetooth, Ethernet, GSM/GPRS.

Built in Microphone and two cameras for audio visual documentation.

20 hour battery life in RTK rover mode with full screen brightness and UHF/GSM. Hot Swappable" and "removable batteries" are concepts of the past.

The internal batteries are field serviceable and can be easily replaced by the user when needed.

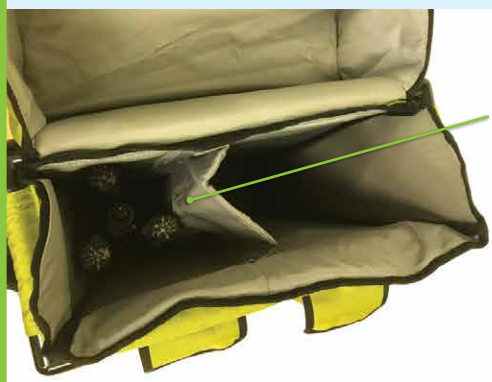
The TRIUMPH-LS, including batteries and pole is the lightest complete GNSS RTK receiver in its class. The total weight of the TRIUMPH-LS RTK system, including radio, controller, pole and 20 hours of internal battery is **2.5 Kg**.

For comparison, the Trimble R10, TSC3 data collector and pole, with about 5 hours of battery life is 3.57 Kg (7.86 lb).

Built in Spectrum analyzer for GNSS and UHF bands and protection against interference.

The J-Pack

It was not our job... You asked for it - we did it!



J-Pod

Landing Pads

Javad.....Bravo!!!!

The J-Pack is nicest bag I have ever seen for surveying. I especially like the pocket in the back and all of the places to tie down equipment and stuff.

Adam Plumley, PLS

Ship date - January 2017

See full video “J-Pack & J-Tip in Use” at our website.