



Locating fence posts...

If you notice the LS center is on the inside face of the post. That is where I will be placing the wire. I staked out each point where a metal tpost will be driven between the larger wooden posts. I will cut the wooden posts to height later. For now I had to climb up on the roof of the buggy to shoot them. I've done about 500 ft of posts so far and they line up great. Much better work flow than the old school way of tying Mason twine to the posts and using that for line and pulling tape or flipping tposts (if you know what I mean). I've flipped a few in my time.

Adam Plumley, PLS



TRIUMPH-3

The new TRIUMPH-3 receiver inherits the best features of our famous TRIUMPH-1M.

Based on our new third generation TRIUMPH chip enclosed in a rugged magnesium alloy housing.



The TRIUMPH-3 receiver can operate as a portable base station for Real-time Kinematic (RTK) applications or as a receiver for post-processing, and as a scientific station collecting information for individual studies, such as ionosphere monitoring and the like.

It includes options for all of the software and hardware features required to perform a wide variety of tasks.



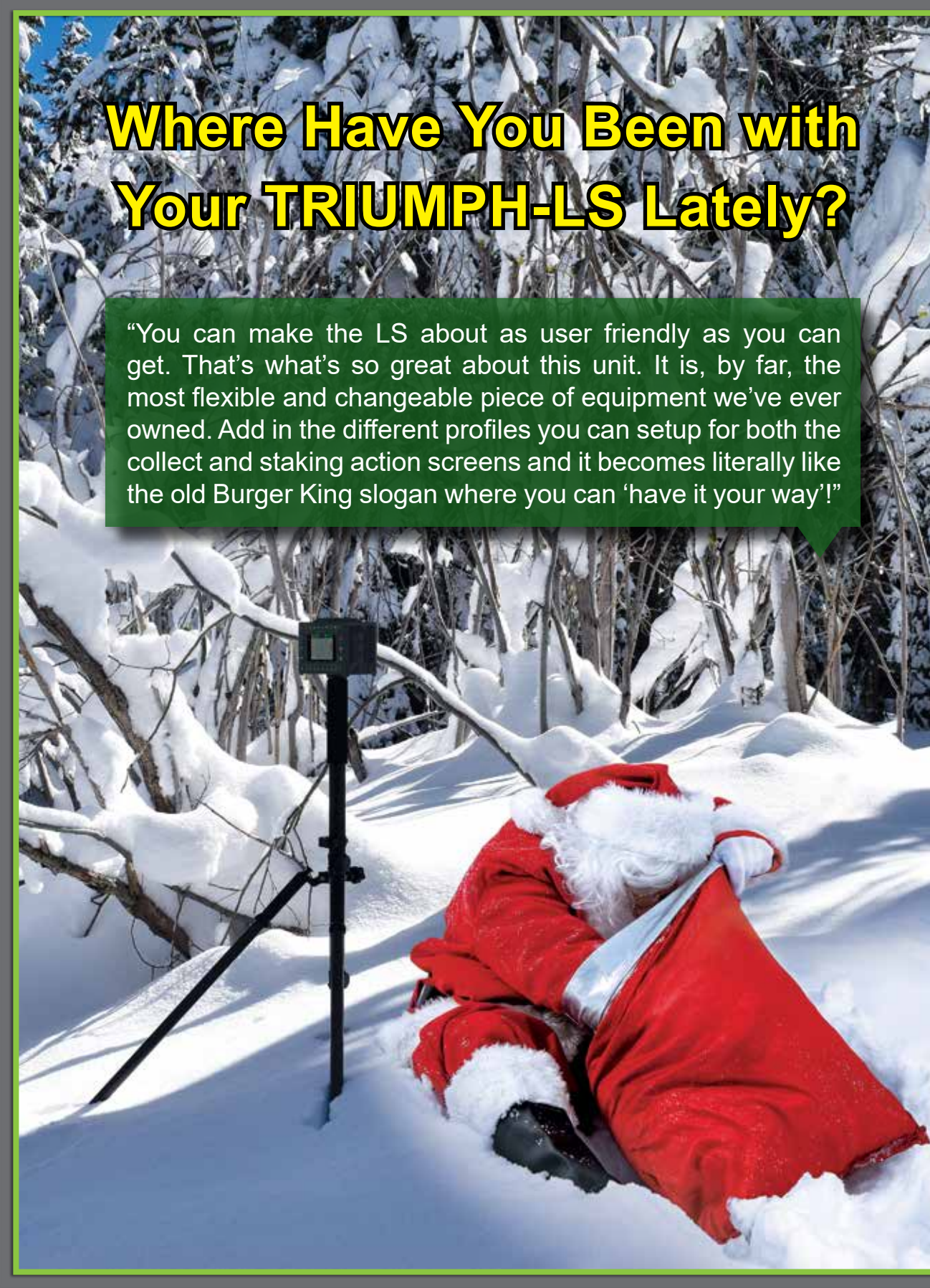
- UHF/Spread Spectrum Radio
- 4G/LTE module
- Wi-Fi 5 GHz and 2.4 GHz (802.11 a, b, g, n, d, e, i)
- Dual-mode Bluetooth and Bluetooth LE
- Full-duplex 10BASE-T/100Base-TX Ethernet port
- High Speed USB 2.0 Host (480 Mbps)
- High Speed USB 2.0 Device (480 Mbps)
- High Capacity microSD Card (microSDHC) up to 128GB Class 10;
- "Lift & Tilt"
- J-Mobile interface

Ideal as a base station

Back

Where Have You Been with Your TRIUMPH-LS Lately?

"You can make the LS about as user friendly as you can get. That's what's so great about this unit. It is, by far, the most flexible and changeable piece of equipment we've ever owned. Add in the different profiles you can setup for both the collect and staking action screens and it becomes literally like the old Burger King slogan where you can 'have it your way!'"



Front

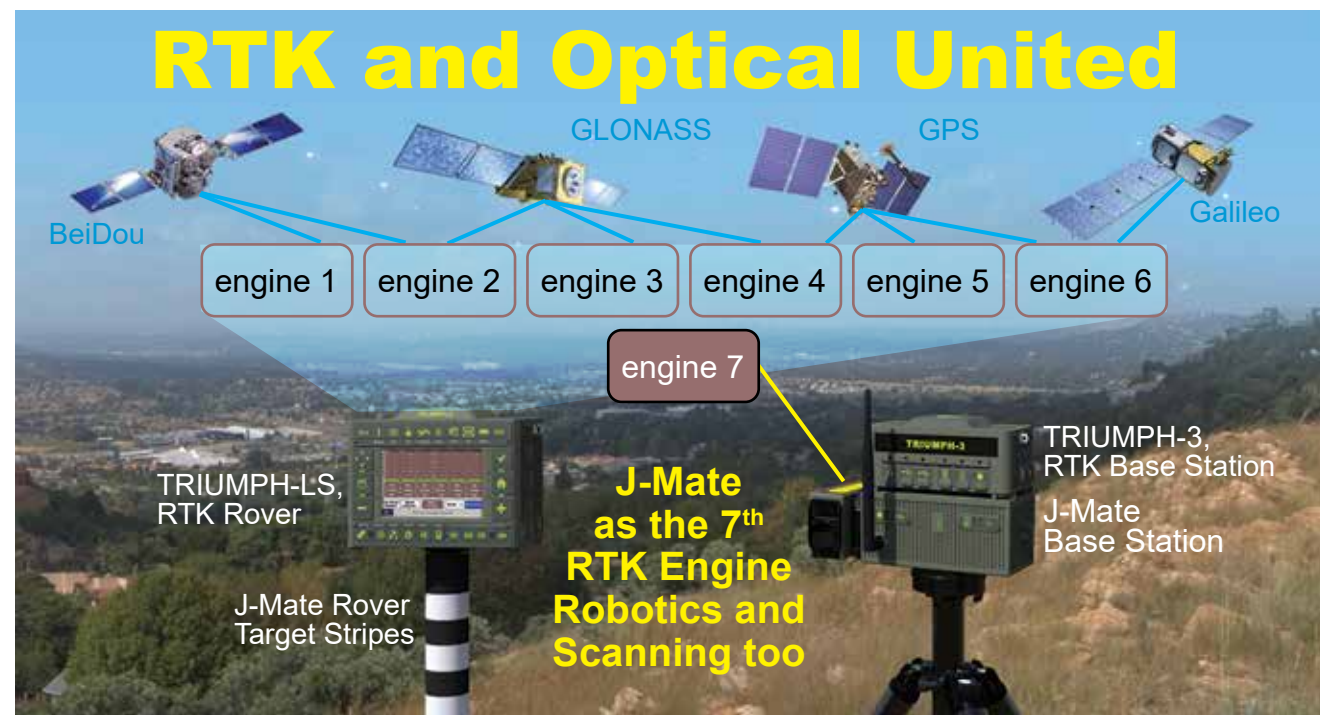


Stephen Drake
TRIUMPH-LS user
and J-Mate Volunteer.

"I don't know if I'd still be in business if it weren't for Javad"



FL



Your Own Complete RTK & Optical

Setup TRIUMPH-3 on top of J-Mate. Set up TRIUMPH-LS on top of the Zebra rod.

TRIUMPH-3 is the RTK base station and TRIUMPH-LS the RTK rover. J-Mate is the optical base station and the Zebra rod is the optical rover.

Now RTK and optical solutions are available simultaneously and can verify each other's solutions. They also can cover each other, when one is not available.

RTK has six engines. We treat the J-Mate solution as the seventh engine of the system.

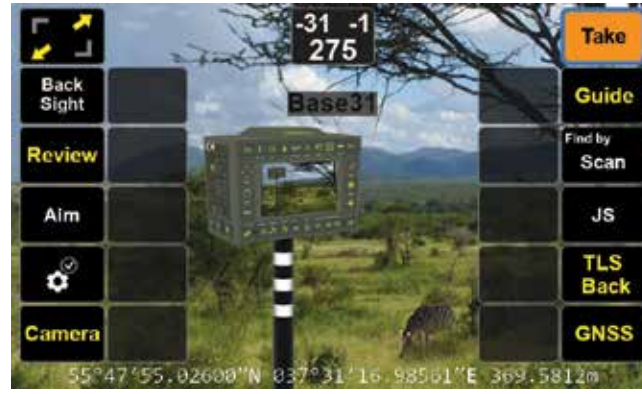
The system is self-sufficient for all jobs. No need to pay RTN service providers for RTK base stations and no need to pay communication service providers. The communications are done via integrated and included Bluetooth, UHF, and Wi-Fi embedded in the system.

Another major advantage is that because your own RTK base station is not far from your rover, RTK solutions will be provided much faster and more reliably.

We added the "Aim" option for stake-out. In this mode J-Mate points to the selected stake point and you follow the laser to reach the intended point. This is in addition to the robotic mode which J-Mate follows your Zebra pole.

At TRIUMPH-LS = 2.13 kg (4.40 lb), TRIUMPH-3 = 1.26 Kg (2.20lb), and J-Mate = 2.17 kg (4.41 lb), the total package of 5.6 kg (11.02 lb), weighs less than one conventional optical total station alone.

J-Mate does have complete geodetically encoded scanning (3 points per second) and robotic features too.



J-Field, the Embedded Controller

J-Field is the embedded application program of TRIUMPH-LS. It has the following unique features for each point surveyed:

- Six parallel RTK engines to maximize solution availability.
- Automatic Engines Resets, verification and validation strategy.
- Several graphical and numerical confidence reports and documentation.
- Voice-to-text conversion for hands free operation and documentation.
- Lift & Tilt and automatic shots for hands free operation.
- Visual Stakeout (Virtual Reality).
- "DPOS it" or "Reverse Shift it" features. The most advanced RTK verification.
- Photogrammetry and angle measurements with embedded cameras.
- Automatic or manual photo documentation.
- Automatic screen shots documentation.
- Audio files for documentation.
- Automatic tilt correction.
- Scanner feature.
- Find objects by their shape, by laser or optical.
- Comprehensive HTML and PDF reports.
- Comprehensive codes, tags and drawing tools.
- Status of all GNSS signals and their quality.
- Over 3,000 Coordinate Systems.
- Automatic and free software update via Internet.



Take Backsight with a Single Shot



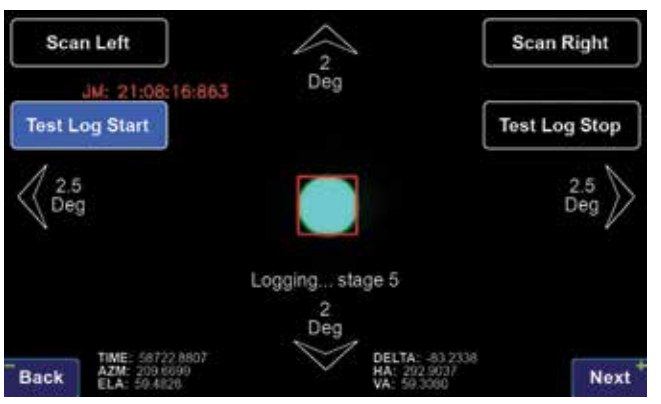
To calibrate the J-Mate, take few seconds of RTK at the Backsight point, and click "Backsight" button. There is no need to locate Occupation Point and the Backsight point, because Occupation point is the RTK Base station and one point is enough to determine the azimuth to calibrate the J-Mate angular encoders.



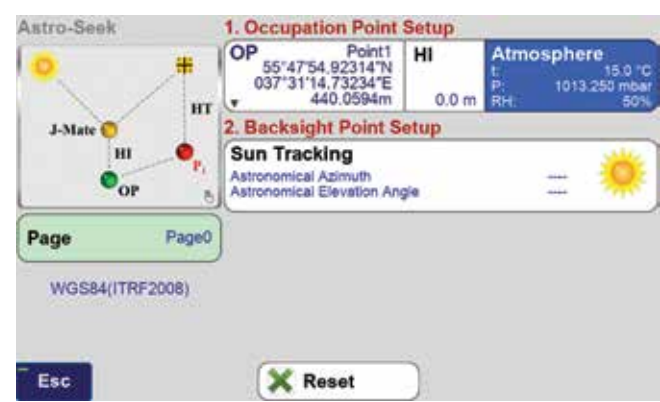
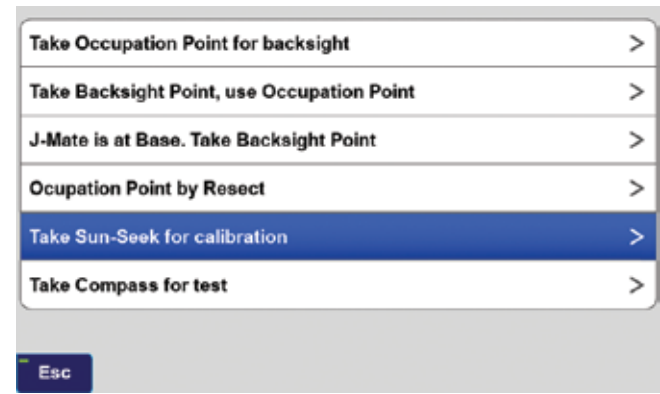
Backsight with Auto SunSeek



Click a button and after a few seconds Backsight will be calibrated with the Sun **AUTOMATICALLY**. Don't forget the Sun filter.



See details at www.javad.com



Light Weight, Low Cost

Costs 1/2, Weighs 1/2 and works much better than conventional total stations and RTK systems.



Complete RTK Base & Rover.
Complete controller and software.
Complete optical system.
Free updates.
Robotic & Scanner...
...all under \$40K

And it all fits in a small carrying bag.

Six RTK Engines Auto VERIFY



Smart assignment of satellite signals to different engines.

This vigorous, automated approach to verifying the fixed ambiguities determined by TRIUMPH-LS gives the user confidence in his results and saves considerable time compared to the methods required to obtain minimal confidence in the fixed ambiguity solutions of other RTK rovers and data collectors on the market today.

The methods required by other systems are not nearly so automated, often requiring the user to manually reset the single engine of his rover, storing another point representing the original point and then manually comparing the two by inverse, all to achieve a single check on the accuracy of the fixed ambiguities. Acquiring more confidence requires manually storing and manually evaluating more points. Conversely, J-Field automatically performs this test, resetting the multiple engines, multiple times (as defined by user), provides an instant graphic display of the test results, and produces one single point upon completion.

