



GPS 16/17 SERIES TECHNICAL SPECIFICATIONS



(GPS 17)



(GPS 16)



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RECORD OF REVISIONS

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1. INTRODUCTION

1.1 CAUTIONS

CAUTION

The GPS system is operated by the government of the United States, which is solely responsible for its accuracy and maintenance. Although the GPS 16/17 series products are precision electronic NAVigation AID (NAVAID), any NAVAID can be misused or misinterpreted, and therefore become unsafe. Use these products at your own risk. To reduce the risk, carefully review and understand all aspects of these Technical Specifications before using the GPS 16/17 series products. When in actual use, carefully compare indications from the GPS to all available navigation sources including the information from other NAVAIDs, visual sightings, charts, etc. For safety, always resolve any discrepancies before continuing navigation.

FCC Compliance

The GPS 16/17 series products comply with Part 15 of the FCC interference limits for Class B digital devices FOR HOME OR OFFICE USE. These limits are designed to provide reasonable protection against harmful interference in a residential installation, and are more stringent than “outdoor” requirements.

Operation of this device is subject to the following conditions: (1) This device may not cause harmful interference, and (2) this device must accept any interference received, including interference that may cause undesired operation.

This equipment generates, uses and can radiate radio frequency energy and, if not installed and used in accordance with the instructions, may cause harmful interference to radio communications. However, there is no guarantee that interference will not occur in a particular installation. If this equipment does cause harmful interference to radio or television reception, which can be determined by turning the equipment off and on, the user is encouraged to try to correct the interference by one or more of the following measures:

- Reorient or relocate the receiving antenna.
- Increase the separation between the equipment and receiver.
- Connect the equipment into an outlet on a circuit different from that to which the receiver is connected.
- Consult the dealer or an experienced radio/TV technician for help.

The GPS 16/17 series products do not contain any user-serviceable parts. Repairs should only be made by an authorized GARMIN service center. Unauthorized repairs or modifications could result in permanent damage to the equipment, and void your warranty and your authority to operate this device under Part 15 regulations.

1.2 OVERVIEW

The GARMIN GPS 16/17 series products are complete GPS sensors including embedded receiver and antenna, designed for a broad spectrum of OEM (Original Equipment Manufacture) system applications. Based on the proven technology found in other GARMIN 12-channel GPS receivers, the GPS 16/17 series products will track up to 12 satellites at a time while providing fast time-to-first-fix, one-second navigation updates and low power consumption. This generation of GPS sensors adds the capability of FAA Wide Area Augmentation System (WAAS) differential GPS. Their far-reaching capability meets the sensitivity requirements of land navigation as well as the dynamics requirements of high-performance aircraft.

These GPS designs utilize the latest technology and high-level circuit integration to achieve superior performance while minimizing space and power requirements. All critical components of the system including the RF/IF receiver hardware and the digital baseband are designed and manufactured by GARMIN to ensure the quality and capability of the GPS. The hardware capability combined with software intelligence makes the GPS 16/17 series products easy to integrate and use.

The GPS 16/17 series products are designed to withstand rugged operating conditions and are completely water-resistant. These are complete GPS receivers that require minimal additional components to be supplied by an OEM or system integrator. A minimum system must provide the GPS with a source of power and a clear view of the GPS satellites. The system may communicate with the GPS via two full-duplex communication channels. Internal FLASH memory allows the GPS to retain critical data such as satellite orbital parameters, last-known position, date and time. End user interfaces such as keyboards and displays are the responsibility of the application designer.

1.3 FEATURES

- 12-channel GPS receiver tracks and uses up to 12 satellites for fast, accurate positioning and low power consumption.
- Differential DGPS capability utilizing real-time WAAS or RTCM corrections yielding 3-5 meter position accuracy (see Technical Specifications).
- Compact, rugged design ideal for applications with minimal space. May be remotely mounted in an out-of-the-way location. Receiver status information can be displayed directly on a chartplotter or PC.
- User initialization is not required. Once installed, unit will automatically transmit navigation data.
- User-configurable navigation mode (2-dimensional or 3-dimensional fix).
- (Not available on GPS 16A nor GPS 17N) Highly accurate one-pulse-per-second (PPS) output for precise timing measurements. Pulse width is configurable in 20 millisecond increments from 20 ms to 980 ms.
- Configurable for binary format carrier phase data output on COM 1 port.
- Flexible input voltage levels of 3.3 Vdc to 6.0 Vdc with over-voltage protection in the GPS 16-LVS, 6.0 Vdc to 40 Vdc in the GPS 16-HVS and GPS 17-HVS, and 8.0 Vdc to 40 Vdc in the GPS 16A and GPS 17N.
- FLASH-based program and non-volatile memory. New software revisions upgradeable through web site download and serial interface. Non-volatile memory does not require battery backup.

1.4 TECHNICAL SPECIFICATIONS

Specifications are subject to change without notice.

1.4.1 Physical Characteristics

1.4.1.1 Color

- GPS 16: Black with white logos (except GPS 16A, which is white with black logos)
- GPS 17: White with black logos

1.4.1.2 Size

- GPS 16: 3.39" (86 mm) diameter, 1.65" (42 mm) high
- GPS 17: 3.39" (86 mm) diameter, 4.25" (108 mm) high

1.4.1.3 Weight

- GPS 16-LVS,
GPS 16-HVS: 6.4 oz. (181 g) without cable;
11.7 oz. (332 g) with 5 meter cable
- GPS 16A: 9.6 oz. (272 g) without cable;
17.6 oz. (500 g) with 5 meter cable
- GPS 17-HVS: 6.7 oz. (190 g) without cable;
16.4 oz. (465 g) with 30 foot cable
- GPS 17N: 6.4 oz. (181 g) without cable;
16.0 oz. (454 g) with 30 foot cable

1.4.1.4 Cable

- GPS 16-LVS,
GPS 16-HVS: Black PVC-jacketed, 5 meter, foil-shielded 8-conductor 28 AWG with RJ-45 termination.
- GPS 16A: White Teflon-jacketed, 5 meter, foil-shielded 5-conductor 22 AWG with bare wire termination
- GPS 17-HVS: White PVC-jacketed, 30 foot, foil-shielded 8-conductor 28 AWG with RJ-45 termination.
- GPS 17N: White PVC-jacketed, 30 foot, foil-shielded 8-conductor 28 AWG with bare wire termination

1.4.2 Electrical Characteristics

1.4.2.1 Input Voltage

- GPS 16-LVS: 3.3 Vdc to 6.0 Vdc regulated, < 100 mV ripple
- GPS 16-HVS,
GPS 17-HVS: 6.0 Vdc to 40 Vdc unregulated
- GPS 16A,
GPS 17N: 8.0 Vdc to 40 Vdc unregulated

1.4.2.2 Input Current

- GPS 16-LVS: 80 mA typical
- GPS 16-HVS,
GPS 17-HVS,
GPS 16A,
GPS 17N: 100 mA @ 6 Vdc (not applicable to GPS 16A nor GPS 17N)
65 mA @ 12 Vdc
28 mA @ 40 Vdc

1.4.2.3 GPS Receiver Sensitivity

- -165 dBW minimum

1.4.3 GPS Performance

1.4.3.1 Receiver

- WAAS enabled; 12 parallel channel GPS receiver continuously tracks and uses up to 12 satellites (up to 11 with PPS active) to compute and update your position.

1.4.3.2 Acquisition Times (Approximate)

- Reacquisition: Less than 2 seconds
- Warm: 15 seconds (all data known)
- Cold: 45 seconds (initial position, time and almanac known, ephemeris unknown)
- AutoLocate™: 5 minutes (almanac known, initial position and time unknown)
- SkySearch: 5 minutes (no data known)

1.4.3.3 Sentence Rate

- (Not applicable to GPS 16A) 1 second default; NMEA 0183 output interval configurable from 1 to 900 seconds in one-second increments
- (GPS 16A only) 1 second independent update rate, propagated every 200 milliseconds

1.4.3.4 Accuracy

- GPS Standard Positioning Service (SPS)
Position: < 15 meters, 95% typical (100 meters with Selective Availability on)
Velocity: 0.1 knot RMS steady state
- DGPS (USCG/RTCM)
Position: 3-5 meters, 95% typical
Velocity: 0.1 knot RMS steady state
- DGPS (WAAS)
Position: < 3 meters, 95% typical
Velocity: 0.1 knot RMS steady state
- PPS Time (Not available on GPS 16A nor GPS 17N):
±1 microsecond at rising edge of PPS pulse (subject to Selective Availability)
- Dynamics: 999 knots velocity (only limited at altitude greater than 60,000 feet), 6g dynamics

1.4.4 Interfaces

- True RS-232 output (TTL output for GPS 16A and GPS 17N) (Port 2 output not used at time of publication), asynchronous serial input compatible with RS-232 or TTL voltage levels, RS-232 polarity.
- User selectable baud rate (300, 600, 1200, 2400, 4800, 9600, 19200) (38400 available for GPS 16A)

1.4.4.1 Port 1

- Configurable between NMEA 0183 Versions 2.00 and 3.00
- ASCII output sentences GPALM, GPGGA, GPGLL, GPGSA, GPGSV, GPRMC, GPVTG (NMEA-approved sentences); PGRMB, PGRME, PGRMF, PGRMM, PGRMT, and PGRMV (GARMIN proprietary sentences)
- NMEA 0183 Outputs (see Section 3.2 for full protocol specifications)
Position, velocity and time
Receiver and satellite status
Differential Reference Station ID and RTCM Data age
Geometry and error estimates
- NMEA 0183 Inputs (see Section 3.1 for full protocol specifications)
Initial position, date and time (not required)
Earth datum and differential mode configuration command, PPS Enable, GPS satellite almanac
- Configurable for binary data output including GPS carrier phase data

1.4.4.2 Port 2

- Real-time Differential Correction input (RTCM SC-104 message types 1, 2, 3, 7 and 9)

1.4.4.3 PPS (Not available on GPS 16A nor GPS 17N)

- 1 Hz pulse, programmable width, 1 μ s accuracy

1.4.4.4 Power Control (Not available on GPS 16A)

- Off: Open circuit
- On: Ground, or pull to low logic level < 0.3 volts

1.4.5 Environmental Characteristics

- Temperature: -30°C to +80°C (Operating); -40°C to +80°C (Storage)

1.5 LIMITED WARRANTY

This GARMIN product is warranted to be free from defects in materials or workmanship for one year from the date of purchase. Within this period, GARMIN will at its sole option, repair or replace any components that fail in normal use. Such repairs or replacement will be made at no charge to the customer for parts or labor, provided that the customer shall be responsible for any transportation cost. This warranty does not cover failures due to abuse, misuse, accident or unauthorized alteration or repairs.

THE WARRANTIES AND REMEDIES CONTAINED HEREIN ARE EXCLUSIVE AND IN LIEU OF ALL OTHER WARRANTIES EXPRESS OR IMPLIED OR STATUTORY, INCLUDING ANY LIABILITY ARISING UNDER ANY WARRANTY OF MERCHANTABILITY OR FITNESS FOR A PARTICULAR PURPOSE, STATUTORY OR OTHERWISE. THIS WARRANTY GIVES YOU SPECIFIC LEGAL RIGHTS, WHICH MAY VARY FROM STATE TO STATE.

IN NO EVENT SHALL GARMIN BE LIABLE FOR ANY INCIDENTAL, SPECIAL, INDIRECT OR CONSEQUENTIAL DAMAGES, WHETHER RESULTING FROM THE USE, MISUSE, OR INABILITY TO USE THIS PRODUCT OR FROM DEFECTS IN THE PRODUCT. Some states do not allow the exclusion of incidental or consequential damages, so the above limitations may not apply to you.

GARMIN retains the exclusive right to repair or replace the unit or software or offer a full refund of the purchase price at its sole discretion. SUCH REMEDY SHALL BE YOUR SOLE AND EXCLUSIVE REMEDY FOR ANY BREACH OF WARRANTY.

To obtain warranty service, contact your local GARMIN authorized dealer. Or call GARMIN Customer Service at one of the numbers shown below, for shipping instructions and an RMA tracking number. The unit should be securely packed with the tracking number clearly written on the outside of the package. The unit should then be sent, freight charges prepaid, to any GARMIN warranty service station. A copy of the original sales receipt is required as the proof of purchase for warranty repairs.

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2. WIRING

2.1 DESCRIPTION

The GPS 16 and GPS 17-HVS sensors utilize an eight-pin RJ-45 plug. The GPS 16A and GPS 17N feature a stripped and pre-tinned cable assemblies (5-wire and 8-wire, respectively) for connection flexibility. The following is a functional description of each wire in the cable assembly.

Table 1. Signal/Wire Descriptions

RJ-45 Pin #	Wire Color	Signal Name	Description
1	Red	POWER	<p>GPS 16-LVS: Regulated +3.3 to +6 Vdc. Typical operating current is 80 mA. An internal 6.8 V transient zener diode and a positive temperature coefficient thermistor protect from transients and over-voltages. With voltages greater than 6.8 Vdc the zener will draw several amps of current through the thermistor, causing it to heat rapidly and eventually power the unit off, unless an external fuse blows first. When proper supply voltages are returned, the thermistor will cool and allow the GPS 16-LVS to operate. The CMOS/TTL output buffers are powered by Vin, therefore a 3.3 Vdc supply will create 3.3 V logic output levels.</p> <p>GPS 16-HVS, GPS 16A, GPS 17-HVS, GPS 17N: Vin can be an unregulated 6.0 Vdc (8.0 Vdc for GPS 16A and GPS 17N) to 40 Vdc, optimized for 12 Vdc. Typical operating power is 800 mW. This voltage drives a switching regulator with a nominal 5.0 Vdc output, which powers the internal linear regulators, and the CMOS output buffers.</p>
2	Black	GROUND	Power and Signal Ground
3	Yellow	REMOTE POWER ON/OFF	(N/A for GPS 16A) External Power Control Input. Active (ON) if less than 0.3 Vdc. Inactive (OFF) if open-circuit. 51 kΩ internal pull-up resistor to the voltage on the POWER input. Activation of this input powers the internal regulators off and drops the supply current below 20 mA in the GPS 16-LVS, and below 1 mA in the GPS 16-HVS, GPS 17-HVS, and GPS 17N. This input is intended to be driven by an open-collector output.
4	Blue	PORT 1 DATA IN	First Serial Asynchronous Input. RS-232 compatible with maximum input voltage range $-25 < V < 25$. This input may also be directly connected to standard 3 to 5 Vdc CMOS logic. The low signal voltage requirement is < 0.9 V, and the high signal voltage requirement is > 2.1 V. Maximum load impedance is 4.7 kΩ. This input may be used to receive serial initialization/configuration data as specified in Section 3.1.
5	White	PORT 1 DATA OUT	First Serial Asynchronous Output. This RS-232 compatible (TTL level on GPS 16A and GPS 17N) output normally provides serial data which is formatted per "NMEA 0183, Version 3.0". This output is also capable of outputting phase data information, see Appendix C for details. The NMEA 0183 baud rate is switchable in the range of 300 to 19200 baud (38400 for GPS 16A). The default baud rate is 19200 for GPS 16A and 4800 for all other products.
6	Gray	PPS	(N/A for GPS 16A and GPS 17N) One-Pulse-Per-Second Output. Typical voltage rise and fall times are 300 ns. Impedance is 250 Ω. Open circuit output voltage is low=0 V and high=Vin in the GPS 16-LVS, and low=0 V and high=5.0 V in the GPS 16-HVS and GPS 17. The default format is a 100 ms wide active-high pulse at a 1 Hz rate, the pulse width is configurable in 20 ms increments. Rising edge is synchronized to the start of each GPS second. This output will provide a nominal 700 mVp-p signal into a 50 Ω load. The pulse time measured at the 50% voltage point will be about 50 ns earlier with a 50 Ω load than with no load.
7	Green	PORT 2 DATA IN	Second Serial Asynchronous Input, electrically identical to PORT 1 DATA IN. This input may be used to receive serial differential GPS data formatted per "RTCM SC-104 Recommended Standards For Differential Navstar GPS Service, Version 2.2" (see Section 3.5 for more details).
8	Violet	PORT 2 DATA OUT	(N/A for GPS 16A) Second Serial Asynchronous Output, electrically identical to PORT 1 DATA OUT. Reserved for future use.

2.2 DIAGRAMS

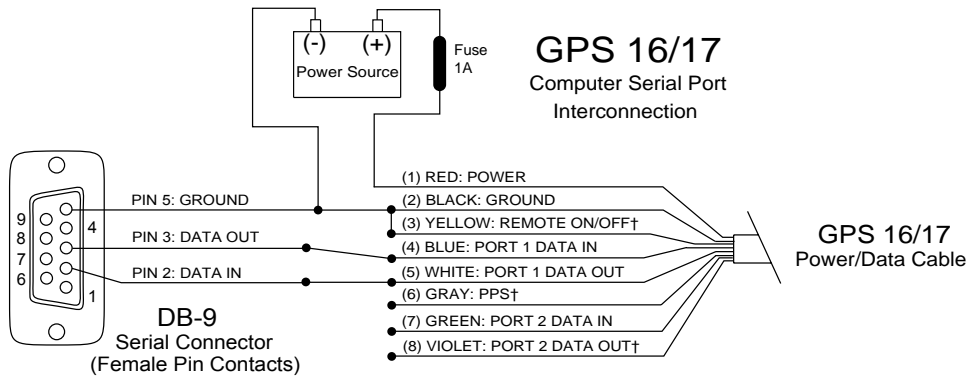


Figure 1. Computer Serial Port Interconnection

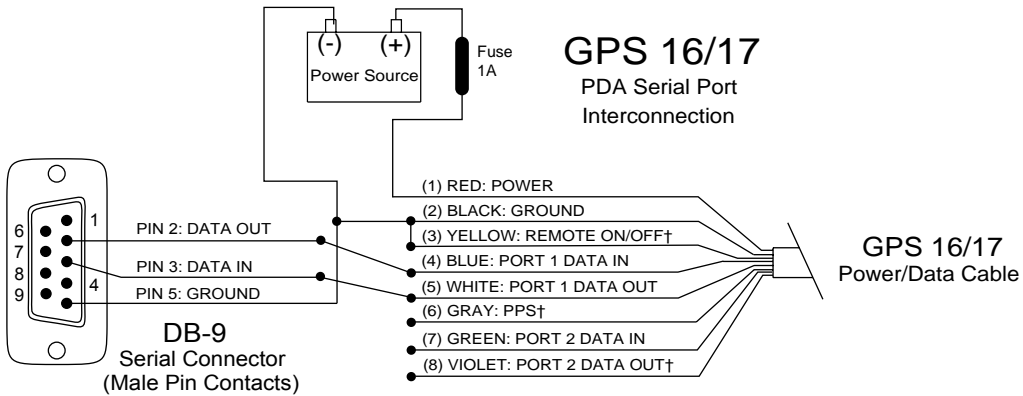


Figure 2. PDA Serial Port Interconnection

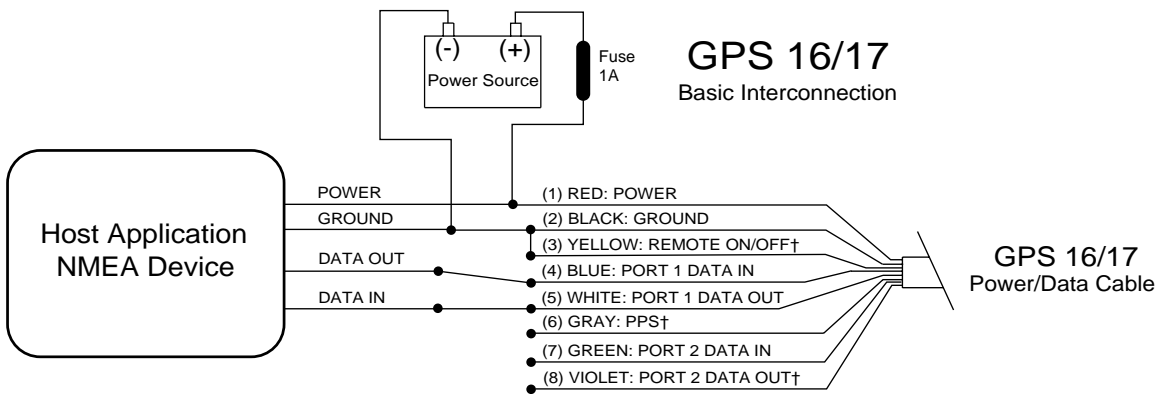


Figure 3. Basic NMEA Device Interconnection

† Not applicable to GPS 16A

3. SOFTWARE INTERFACE

The GPS 16/17 series products interface protocol design on COM 1 is based on the National Marine Electronics Association's NMEA 0183 ASCII interface specification. The COM 2 port can receive differential GPS (DGPS) correction data using the Radio Technical Commission for Maritime Services' RTCM SC-104 standard. These standards are fully defined in "NMEA 0183, Version 3.0" (copies may be obtained from NMEA, www.nmea.org) and "RTCM Recommended Standards For Differential Navstar GPS Service, Version 2.2, RTCM Special Committee No. 104" (copies may be obtained from RTCM, www.rtcn.org).

The GPS 16/17 series products interface protocol, in addition to transmitting navigation information as defined by NMEA 0183, transmits additional information using the convention of GARMIN proprietary sentences.

Binary phase data information can alternatively be output on the COM 1 port; see Appendix C for details.

The following sections describe the NMEA 0183 data format of each sentence transmitted and received by the GPS 16/17 series products. The baud rate selection, one-pulse-per-second output interfaces and RTCM differential GPS input are also described.

3.1 RECEIVED NMEA 0183 SENTENCES

The subsequent paragraphs define the sentences that can be received on the GPS sensors' COM 1 port. Null fields in the configuration sentence indicate no change in the particular configuration parameter. All sentences received by the GPS sensor must be terminated with <CR><LF>, the ASCII characters for carriage return (0D hexadecimal) and line feed (0A hexadecimal). The checksum *hh is used for parity checking data and is not required, but is recommended for use in environments containing high electromagnetic noise. It is generally not required in normal PC environments. When used, the parity bytes (hh) are the ASCII representation of the exclusive-or (XOR) sum of all the characters between the "\$" and "*" characters, non-inclusive. Sentences may be truncated by <CR><LF> after any data field and valid fields up to that point will be acted on by the GPS sensor.

3.1.1 Almanac Information (ALM)

The \$GPALM sentence can be used to initialize the GPS sensor's stored almanac information in the unlikely event of non-volatile memory loss, or after storage of greater than six months without tracking GPS satellites.

\$GPALM,<1>,<2>,<3>,<4>,<5>,<6>,<7>,<8>,<9>,<10>,<11>,<12>,<13>,<14>,<15>*hh<CR><LF>

<1>	Total number of ALM sentences to be transmitted by the GPS sensor during almanac download. This field can be null or any number when sending almanac to the GPS sensor.
<2>	Number of current ALM sentence. This field can be null or any number when sending almanac to the GPS sensor.
<3>	Satellite PRN number, 01 to 32
<4>	GPS week number
<5>	SV health, bits 17-24 of each almanac page
<6>	Eccentricity
<7>	Almanac reference time
<8>	Inclination angle
<9>	Rate of right ascension
<10>	Root of semi major axis
<11>	Omega, argument of perigee
<12>	Longitude of ascension node
<13>	Mean anomaly
<14>	af0 clock parameter
<15>	af1 clock parameter

3.1.2 Sensor Initialization Information (PGRMI)

The \$PGRMI sentence provides information used to initialize the GPS sensor's set position and time used for satellite acquisition. Receipt of this sentence by the GPS sensor causes the software to restart the satellite acquisition process. If there are no errors in the sentence, it will be echoed upon receipt. If an error is detected, the echoed PGRMI sentence will contain the current default values. Current PGRMI defaults (with the exception of the Receiver Command, which is a command rather than a mode) can also be obtained by sending \$PGRMIE to the GPS sensor.

\$PGRMI,<1>,<2>,<3>,<4>,<5>,<6>,<7>*hh<CR><LF>

<1>	Latitude, ddmm.mmm format (leading zeros must be transmitted)
<2>	Latitude hemisphere, N or S
<3>	Longitude, dddmm.mmm format (leading zeros must be transmitted)
<4>	Longitude hemisphere, E or W
<5>	Current UTC date, ddmmyy format
<6>	Current UTC time, hhmmss format
<7>	Receiver Command, A = Auto Locate, R = Unit Reset

3.1.3 Sensor Configuration Information (PGRMC)

The \$PGRMC sentence provides information used to configure the GPS sensor's operation. Configuration parameters are stored in non-volatile memory and retained between power cycles. The GPS sensor will echo this sentence upon its receipt if no errors are detected. If an error is detected, the echoed PGRMC sentence will contain the current default values. Current default values can also be obtained by sending \$PGRMCE to the GPS sensor.

\$PGRMC,<1>,<2>,<3>,<4>,<5>,<6>,<7>,<8>,<9>,<10>,<11>,<12>,<13>,<14>*hh<CR><LF>

<1>	Fix mode, A = automatic, 2 = 2D exclusively (host system must supply altitude), 3 = 3D exclusively
<2>	Altitude above/below mean sea level, -1500.0 to 18000.0 meters
<3>	Earth datum index. If the user datum index (96) is specified, fields <4> through <8> must contain valid values. Otherwise, fields <4> through <8> must be null. Refer to Appendix A for a list of earth datums and the corresponding earth datum index.
<4>	User earth datum semi-major axis, 6360000.000 to 6380000.000 meters (.001 meters resolution)
<5>	User earth datum inverse flattening factor, 285.0 to 310.0 (10 ⁻⁹ resolution)
<6>	User earth datum delta x earth centered coordinate, -5000.0 to 5000.0 meters (1 meter resolution)
<7>	User earth datum delta y earth centered coordinate, -5000.0 to 5000.0 meters (1 meter resolution)
<8>	User earth datum delta z earth centered coordinate, -5000.0 to 5000.0 meters (1 meter resolution)
<9>	Differential mode, A = automatic (output DGPS data when available, non-DGPS otherwise), D = differential exclusively (output only differential fixes)
<10>	NMEA 0183 Baud rate, 1 = 1200, 2 = 2400, 3 = 4800, 4 = 9600, 5 = 19200, 6 = 300, 7 = 600
<11>	Velocity filter, 0 = No filter, 1 = Automatic filter, 2-255 = Filter time constant (e.g., 10 = 10 second filter)
<12>	PPS mode, 1 = No PPS, 2 = 1 Hz
<13>	PPS pulse length, 0-48 = (n+1)*20 ms. Example: n = 4 corresponds to a 100 ms wide pulse
<14>	Dead reckoning valid time 1-30 (sec)

All configuration changes take effect after receipt of a valid value except baud rate and PPS mode. Baud rate and PPS mode changes take effect on the next power cycle or an external reset event.

3.1.4 Additional Sensor Configuration Information (PGRMC1)

The \$PGRMC1 sentence provides additional information used to configure the GPS sensor operation. Configuration parameters are stored in non-volatile memory and retained between power cycles. The GPS sensor will echo this sentence upon its receipt if no errors are detected. If an error is detected, the echoed PGRMC1 sentence will contain the current default values. Current default values can also be obtained by sending \$PGRMC1E to the GPS sensor.

\$PGRMC1,<1>,<2>,<3>,<4>,<5>,<6>,<7>,<8>,<9>*hh<CR><LF>

<1>	NMEA 0183 output time 1-900 (sec) (not applicable to GPS 16A)
<2>	Binary Phase Output Data, 1 = Off, 2 = On.
<3>	Position pinning, 1 = Off, 2 = On
<4>	DGPS beacon frequency – 0.0, 283.5 – 325.0 kHz in 0.5 kHz steps
<5>	DGPS beacon bit rate – 0, 25, 50, 100, or 200 bps
<6>	DGPS beacon scanning, 1 = Off, 2 = On
<7>	NMEA 0183 version 3.00 mode indicator, 1 = Off, 2 = On
<8>	DGPS mode, A = Automatic, W = WAAS Only, R = RTCM Only, N = None (DGPS disabled)
<9>	Power Save Mode, P = Power Save mode, N = Normal

At power up or external reset, a stored beacon frequency other than 0.0 causes the GPS sensor to tune the beacon receiver. Configuration changes take effect immediately, with the exception of Binary Phase Output Data, which takes effect on the next power cycle or a reset event. A reset can be commanded by sending the sentence “\$PGRMI,,,,,,R” (refer to section 3.1.2). If the GPS sensor is in the Binary data mode, it is necessary to send the following eight-byte data stream to the COM 1 input, to temporarily change the data format to NMEA 0183, and then follow by sending a PGRMC1 sentence that turns off the Binary Phase Output Data format:

10 0A 02 26 00 CE 10 03 (Hexadecimal)

3.1.5 Output Sentence Enable/Disable (PGRMO)

The \$PGRMO sentence provides the ability to enable and disable specific output sentences. The following sentences are enabled at the factory: GPGGGA, GPGSA, GPGSV, GPRMC, PGRMB, PGRME, PGRMM, PGRMT and PSLIB.

\$PGRMO,<1>,<2>*hh<CR><LF>

<1>	Target sentence description (e.g., PGRMT, GPGSV, etc.)
<2>	Target sentence mode, where: 0 = disable specified sentence 1 = enable specified sentence 2 = disable all output sentences (except PSLIB) 3 = enable all output sentences (except GPALM) 4 = restore factory default output sentences

The following notes apply to the PGRMO input sentence:

1. If the target sentence mode is ‘2’ (disable all), ‘3’ (enable all), or ‘4’ (restore defaults), the target sentence description is not checked for validity. In this case, an empty field is allowed (e.g., \$PGRMO,,3), or the mode field may contain from 1 to 5 characters.
2. If the target sentence mode is ‘0’ (disable) or ‘1’ (enable), the target sentence description field must be an identifier for one of the sentences that can be output by the GPS sensor.
3. If either the target sentence mode field or the target sentence description field is not valid, the PGRMO sentence will have no effect.
4. \$PGRMO,GPALM,1 will cause the GPS sensor to transmit all stored almanac information. All other NMEA 0183 sentence transmission will be temporarily suspended.
5. \$PGRMO,,G will cause the COM 1 port to change to GARMIN Data Transfer format for the duration of the power cycle. The GARMIN mode is required for GPS 16/17 series product software updates.

3.1.6 Tune DGPS Beacon Receiver (PSLIB)

The \$PSLIB sentence provides the ability to tune a GARMIN GBR 21, GBR 23 or equivalent beacon receiver.

\$PSLIB,<1>,<2>*hh<CR><LF>

<1>	Beacon tune frequency, 0.0, 283.5 – 325.0 kHz in 0.5 kHz steps
<2>	Beacon bit rate, 0, 25, 50, 100, or 200 bps

If valid data is received, the GPS sensor will store it in the EEPROM and echo the PSLIB command to the beacon receiver. If the GPS sensor is using any stored beacon frequency other than 0.0, it will tune the beacon receiver once immediately after power up or external reset.

3.2 TRANSMITTED NMEA 0183 SENTENCES

The subsequent paragraphs define the sentences that can be transmitted on COM 1 by the GPS sensor.

3.2.1 Sentence Transmission Rate

Sentences are transmitted with respect to the user selected baud rate.

The GPS sensor will transmit each sentence (except where noted in particular transmitted sentence descriptions) at a periodic rate based on the user selected baud rate and user selected output sentences. The GPS sensor will transmit the selected sentences contiguously. The length of the transmission can be determined by the following equation and Tables 2 and 3:

$$\text{length of transmission} = \frac{\text{total characters to be transmitted}}{\text{characters transmitted per second}}$$

Table 2. NMEA 0183 Output Sentence Order and Size

Sentence	Output by Default?	Maximum Characters
GPRMC	✓	74
GPGGA	✓	82
GPGSA	✓	66
GPGSV	✓	70
PGRME	✓	35
GPGLL		44
GPVTG		42
PGRMV		32
PGRMF		82
PGRMB	✓*	40
PGRMM	✓	32
PGRMT	Once per minute	50

* Except GPS 16A

Table 3. Characters per Second for Available Baud Rates

Baud	Characters per Second
300	30
600	60
1200	120
2400	240
4800	480
9600	960
19200	1920
38400**	3840

** GPS 16A only

The maximum number of fields allowed in a single sentence is 82 characters including delimiters. Values in the table include the sentence start delimiter character "\$" and the termination delimiter <CR><LF>. The factory set defaults will result in a once per second transmission at the NMEA 0183 specification transmission rate of 4800 baud.

3.2.1.1 Products Other than GPS 16A

Regardless of the selected baud rate, the information transmitted by the GPS sensor is referenced to the one-pulse-per-second output pulse immediately preceding the GPRMC sentence, or whichever sentence is output first in the burst (see Table 2 above).

3.2.1.2 GPS 16A

Sentences are transmitted at a fixed 200-millisecond interval.

3.2.2 Transmitted Time

The GPS sensor outputs UTC (Coordinated Universal Time) date and time of day in the transmitted sentences. Prior to the initial position fix, the on-board clock provides the date and time of day. After the initial position fix, the date and time of day are calculated using GPS satellite information and are synchronized with the one-pulse-per-second output.

The GPS sensor uses information obtained from the GPS satellites to add or delete UTC leap seconds and correct the transmitted date and time of day. The transmitted date and time of day for leap second correction follow the guidelines in “*National Institute of Standards and Technology Special Publication 432 (Revised 1990)*” (for sale by the Superintendent of Documents, U.S. Government Printing Office, Washington, D.C., 20402, U.S.A.).

When a positive leap second is required, the second is inserted beginning at 23h 59m 60s of the last day of a month and ending at 0h 0m 0s of the first day of the following month. The minute containing the leap second is 61 seconds long. The GPS sensor would have transmitted this information for the leap second added December 31, 1989 as follows:

Date	Time
311289	235959
311289	235960
010190	000000

If a negative leap second should be required, one second will be deleted at the end of some UTC month. The minute containing the leap second will be only 59 seconds long. In this case, the GPS sensor will not transmit the time of day 23h 59m 59s for the day from which the leap second is removed.

3.2.3 Global Positioning System Almanac Data (ALM)

Almanac sentences are not normally transmitted. Almanac transmission can be initiated by sending the GPS sensor a \$PGRMO,GPALM,1 command. Upon receipt of this command the GPS sensor will transmit available almanac information on GPALM sentences. During the transmission of almanac sentences other NMEA 0183 data output will be temporarily suspended.

\$GPALM,<1>,<2>,<3>,<4>,<5>,<6>,<7>,<8>,<9>,<10>,<11>,<12>,<13>,<14>,<15>*hh<CR><LF>

<field information> can be found in section 3.1.1.

3.2.4 Global Positioning System Fix Data (GGA)

\$GPGGA,<1>,<2>,<3>,<4>,<5>,<6>,<7>,<8>,<9>,M,<10>,M,<11>,<12>*hh<CR><LF>

<1>	UTC time of position fix, hhmmss format
<2>	Latitude, ddmm.mmmm format (leading zeros will be transmitted) (5 digits of precision on GPS 16A)
<3>	Latitude hemisphere, N or S
<4>	Longitude, dddmm.mmmm format (leading zeros will be transmitted) (5 digits of precision on GPS 16A)
<5>	Longitude hemisphere, E or W
<6>	GPS quality indication, 0 = fix not available, 1 = Non-differential GPS fix available, 2 = Differential GPS (DGPS) fix available, 6 = Estimated
<7>	Number of satellites in use, 00 to 12 (leading zeros will be transmitted)
<8>	Horizontal dilution of precision, 0.5 to 99.9
<9>	Antenna height above/below mean sea level, -9999.9 to 99999.9 meters
<10>	Geoidal height, -999.9 to 9999.9 meters
<11>	Differential GPS (RTCM SC-104) data age, number of seconds since last valid RTCM transmission (null if not an RTCM DGPS fix)
<12>	Differential Reference Station ID, 0000 to 1023 (leading zeros will be transmitted, null if not an RTCM DGPS fix)

3.2.5 GPS DOP and Active Satellites (GSA)

\$GPGSA,<1>,<2>,<3>,<3>,<3>,<3>,<3>,<3>,<3>,<3>,<3>,<3>,<3>,<3>,<4>,<5>,<6>*hh<CR><LF>

<1>	Mode, M = manual, A = automatic
<2>	Fix type, 1 = not available, 2 = 2D, 3 = 3D
<3>	PRN number, 01 to 32, of satellite used in solution, up to 12 transmitted (leading zeros will be transmitted)
<4>	Position dilution of precision, 0.5 to 99.9
<5>	Horizontal dilution of precision, 0.5 to 99.9
<6>	Vertical dilution of precision, 0.5 to 99.9

3.2.6 GPS Satellites in View (GSV)

\$GPGSV,<1>,<2>,<3>,<4>,<5>,<6>,<7>,...<4>,<5>,<6>,<7>*hh<CR><LF>

<1>	Total number of GSV sentences to be transmitted
<2>	Number of current GSV sentence
<3>	Total number of satellites in view, 00 to 12 (leading zeros will be transmitted)
<4>	Satellite PRN number, 01 to 32 (leading zeros will be transmitted)
<5>	Satellite elevation, 00 to 90 degrees (leading zeros will be transmitted)
<6>	Satellite azimuth, 000 to 359 degrees, true (leading zeros will be transmitted)
<7>	Signal to noise ratio (C/No) 00 to 99 dB, null when not tracking (leading zeros will be transmitted)

NOTE: Items <4>,<5>,<6> and <7> repeat for each satellite in view to a maximum of four (4) satellites per sentence. Additional satellites in view information must be sent in subsequent bursts of NMEA 0183 data. These fields will be null if unused.

3.2.7 Recommended Minimum Specific GPS/TRANSIT Data (RMC)

\$GPRMC,<1>,<2>,<3>,<4>,<5>,<6>,<7>,<8>,<9>,<10>,<11>,<12>*hh<CR><LF>

<1>	UTC time of position fix, hhmmss format
<2>	Status, A = Valid position, V = NAV receiver warning
<3>	Latitude, ddmm.mmmm format (leading zeros will be transmitted) (5 digits of precision on GPS 16A)
<4>	Latitude hemisphere, N or S
<5>	Longitude, dddmm.mmmm format (leading zeros will be transmitted) (5 digits of precision on GPS 16A)
<6>	Longitude hemisphere, E or W
<7>	Speed over ground, 000.0 to 999.9 knots (leading zeros will be transmitted)
<8>	Course over ground, 000.0 to 359.9 degrees, true (leading zeros will be transmitted)
<9>	UTC date of position fix, ddmmyy format
<10>	Magnetic variation, 000.0 to 180.0 degrees (leading zeros will be transmitted)
<11>	Magnetic variation direction, E or W (westerly variation adds to true course)
<12>	Mode indicator (only output if NMEA 0183 version 3.00 active), A = Autonomous, D = Differential, E = Estimated, N = Data not valid

3.2.8 Track Made Good and Ground Speed (VTG)

\$GPVTG,<1>,T,<2>,M,<3>,N,<4>,K,<5>*hh<CR><LF>

<1>	True course over ground, 000 to 359 degrees (leading zeros will be transmitted)
<2>	Magnetic course over ground, 000 to 359 degrees (leading zeros will be transmitted)
<3>	Speed over ground, 000.0 to 999.9 knots (leading zeros will be transmitted)
<4>	Speed over ground, 0000.0 to 1851.8 kilometers per hour (leading zeros will be transmitted)
<5>	Mode indicator (only output if NMEA 0183 version 3.00 active), A = Autonomous, D = Differential, E = Estimated, N = Data not valid

3.2.9 Geographic Position (GLL)

\$GPGLL,<1>,<2>,<3>,<4>,<5>,<6>,<7>*hh<CR><LF>

<1>	Latitude, ddmm.mmmm format (leading zeros will be transmitted) (5 digits of precision on GPS 16A)
<2>	Latitude hemisphere, N or S
<3>	Longitude, dddmm.mmmm format (leading zeros will be transmitted) (5 digits of precision on GPS 16A)
<4>	Longitude hemisphere, E or W
<5>	UTC time of position fix, hhmmss format
<6>	Status, A = Valid position, V = NAV receiver warning
<7>	Mode indicator (only output if NMEA 0183 version 3.00 active), A = Autonomous, D = Differential, E = Estimated, N = Data not valid

3.2.10 Estimated Error Information (PGRME)

\$PGRME,<1>,M,<2>,M,<3>,M*hh<CR><LF>

<1>	Estimated horizontal position error (HPE), 0.0 to 999.9 meters
<2>	Estimated vertical position error (VPE), 0.0 to 999.9 meters
<3>	Estimated position error (EPE), 0.0 to 999.9 meters

3.2.11 GPS Fix Data Sentence (PGRMF)

\$PGRMF,<1>,<2>,<3>,<4>,<5>,<6>,<7>,<8>,<9>,<10>,<11>,<12>,<13>,<14>,<15>*hh<CR><LF>

<1>	GPS week number (0 - 1023)
<2>	GPS seconds (0 - 604799)
<3>	UTC date of position fix, ddmmyy format
<4>	UTC time of position fix, hhmmss format
<5>	GPS leap second count
<6>	Latitude, ddmm.mmmm format (leading zeros will be transmitted) (5 digits of precision on GPS 16A)
<7>	Latitude hemisphere, N or S
<8>	Longitude, dddmm.mmmm format (leading zeros will be transmitted) (5 digits of precision on GPS 16A)
<9>	Longitude hemisphere, E or W
<10>	Mode, M = manual, A = automatic
<11>	Fix type, 0 = no fix, 1 = 2D fix, 2 = 3D fix
<12>	Speed over ground, 0 to 1851 kilometers/hour
<13>	Course over ground, 0 to 359 degrees, true
<14>	Position dilution of precision, 0 to 9 (rounded to nearest integer value)
<15>	Time dilution of precision, 0 to 9 (rounded to nearest integer value)

3.2.12 Map Datum (PGRMM)

The GARMIN Proprietary sentence \$PGRMM gives the name of the map datum currently in use by the GPS sensor. This information is used by the GARMIN MapSource real-time plotting application.

\$PGRMM,<1>*hh<CR><LF>

<1>	Name of map datum currently in use (variable length field, e.g., "WGS 84")
-----	--

3.2.13 Sensor Status Information (PGRMT)

The GARMIN Proprietary sentence \$PGRMT gives information concerning the status of the GPS sensor. This sentence is transmitted once per minute regardless of the selected baud rate.

\$PGRMT,<1>,<2>,<3>,<4>,<5>,<6>,<7>,<8>,<9>*hh<CR><LF>

<1>	Product, model and software version (variable length field, e.g., "GPS 17 VER 2.05")
<2>	ROM checksum test, P = pass, F = fail
<3>	Receiver failure discrete, P = pass, F = fail
<4>	Stored data lost, R = retained, L = lost
<5>	Real time clock lost, R = retained, L = lost
<6>	Oscillator drift discrete, P = pass, F = excessive drift detected
<7>	Data collection discrete, C = collecting, null if not collecting
<8>	GPS sensor temperature in degrees C
<9>	GPS sensor configuration data, R = retained, L = lost

3.2.14 3D velocity Information (PGRMV)

\$PGRMV,<1>,<2>,<3>*hh<CR><LF>

<1>	True east velocity, 514.4 to 514.4 meters/second
<2>	True north velocity, 514.4 to 514.4 meters/second
<3>	Up velocity, 999.9 to 9999.9 meters/second

3.2.15 DGPS Beacon Information (PGRMB)

\$PGRMB,<1>,<2>,<3>,<4>,<5>,K,<6>,<7>*hh<CR><LF>

<1>	Beacon tune frequency, 0.0, 283.5 – 325.0 kHz in 0.5 kHz steps
<2>	Beacon bit rate, 0, 25, 50, 100, or 200 bps
<3>	Beacon SNR, 0 to 31
<4>	Beacon data quality, 0 to 100
<5>	Distance to beacon reference station in kilometers
<6>	Beacon receiver communication status (0 = Check Wiring, 1 = No Signal, 2 = Tuning, 3 = Receiving, 4 = Scanning)
<7>	DGPS fix source (R = RTCM, W = WAAS, N = Non-DGPS Fix)
<8>	DGPS mode, A = Automatic, W = WAAS Only, R = RTCM Only, N = None (DGPS disabled)

3.3 BAUD RATE SELECTION

Baud rate selection can be performed by sending the appropriate configuration sentence to the GPS sensor as described in the \$PGRMC section 3.1.3, field <10>.

3.4 ONE-PULSE-PER-SECOND (PPS) OUTPUT (NOT AVAILABLE ON GPS 16A NOR GPS 17N)

The highly accurate one-pulse-per-second (PPS) output is provided for applications requiring precise timing measurements. The signal is generated after the initial position fix has been calculated and continues until power down. The rising edge of the signal is synchronized to the start of each GPS second.

Regardless of the selected baud rate, the information transmitted by the GPS 16/17 series products is referenced to the pulse immediately preceding the NMEA 0183 RMC sentence.

The accuracy of the one-pulse-per-second output is maintained only while the GPS 16/17 series products can compute a valid position fix. To obtain the most accurate results, the one-pulse-per-second output should be calibrated against a local time reference to compensate for cable and internal receiver delays and the local time bias.

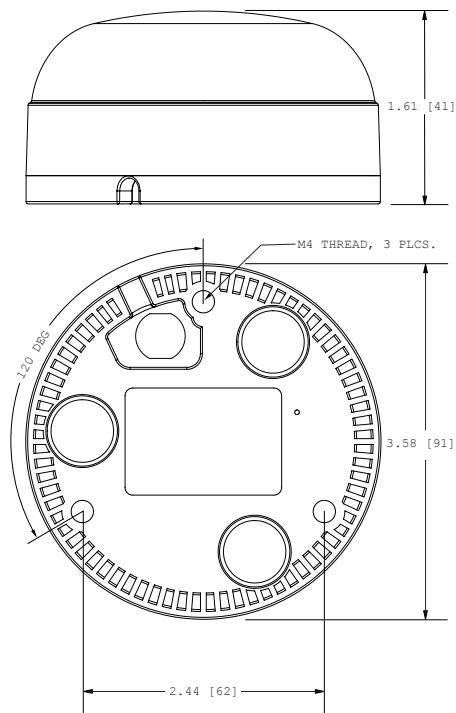
The default pulse width is 100 ms, however; it may be programmed in 20 ms increments between 20 ms and 980 ms as described in \$PGRMC section 3.1.3, field <13>.

3.5 RECEIVED RTCM DATA

Position accuracy of less than 5 meters can be achieved with the GPS 16/17 series products by using Differential GPS (DGPS) real-time pseudo-range correction data in RTCM SC-104 format, with message types 1, 2, 3, 7, and 9. These corrections can be received by the GPS 16/17 series products on COM 2. The RTCM data must be received at the same baud rate as the COM 1 port. For details on the SC-104 format, refer to RTCM Paper 134-89/SC 104-68 by the Radio Technical Commission for Maritime Services.

4. MECHANICAL CHARACTERISTICS & MOUNTING

4.1 GPS 16



NOTE: DIMENSIONS IN INCHES [MM]

Figure 4. GPS 16 Dimensions

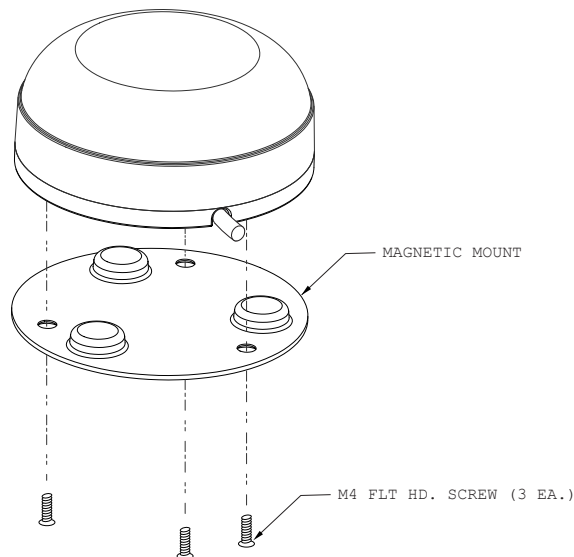
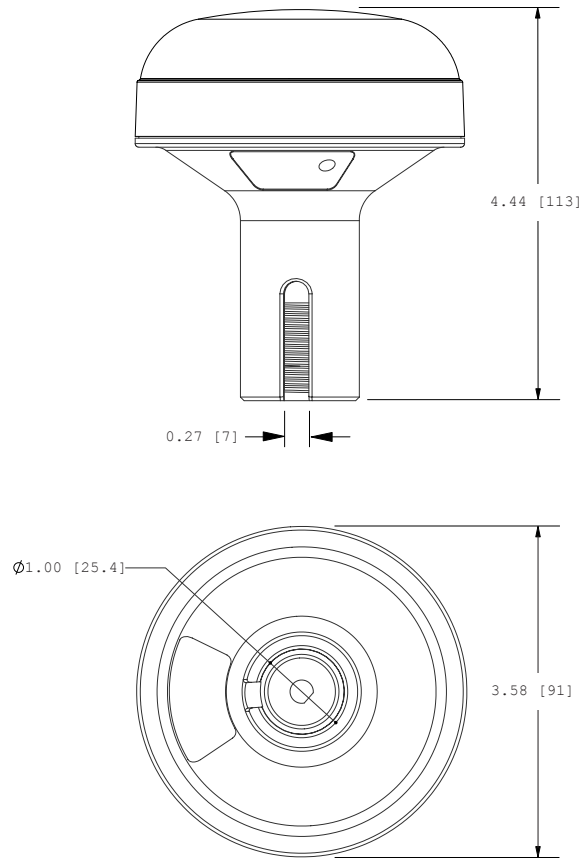


Figure 5. GPS 16 Magnetic Mount Attachment

4.2 GPS 17



NOTE: DIMENSIONS IN INCHES [MM]

Figure 6. GPS 17 Dimensions

Appendix A

Earth Datums

The following is a list of the GARMIN GPS 16/17 series product earth datum indices and the corresponding earth datum name (including the area of application):

0	ADINDAN - Ethiopia, Mali, Senegal, Sudan
1	AFGOOYE - Somalia
2	AIN EL ABD 1970 - Bahrain Island, Saudi Arabia
3	ANNA 1 ASTRO 1965 - Cocos Island
4	ARC 1950 - Botswana, Lesotho, Malawi, Swaziland, Zaire, Zambia, Zimbabwe
5	ARC 1960 - Kenya, Tanzania
6	ASCENSION ISLAND 1958 - Ascension Island
7	ASTRO BEACON "E" - Iwo Jima Island
8	AUSTRALIAN GEODETIC 1966 - Australia, Tasmania Island
9	AUSTRALIAN GEODETIC 1984 - Australia, Tasmania Island
10	ASTRO DOS 71/4 - St. Helena Island
11	ASTRONOMIC STATION 1952 - Marcus Island
12	ASTRO B4 SOROL ATOLL - Tern Island
13	BELLEVUE (IGN) - Efate and Erromango Islands
14	BERMUDA 1957 - Bermuda Islands
15	BOGOTA OBSERVATORY - Colombia
16	CAMPO INCHAUSPE - Argentina
17	CANTON ASTRO 1966 - Phoenix Islands
18	CAPE CANAVERAL - Florida, Bahama Islands
19	CAPE - South Africa
20	CARTHAGE - Tunisia
21	CHATHAM 1971 - Chatham Island (New Zealand)
22	CHUA ASTRO - Paraguay
23	CORREGO ALEGRE - Brazil
24	DJAKARTA (BATAVIA) - Sumatra Island (Indonesia)
25	DOS 1968 - Gizo Island (New Georgia Islands)
26	EASTER ISLAND 1967 - Easter Island
27	EUROPEAN 1950 - Austria, Belgium, Denmark, Finland, France, Germany, Gibraltar, Greece, Italy, Luxembourg, Netherlands, Norway, Portugal, Spain, Sweden, Switzerland
28	EUROPEAN 1979 - Austria, Finland, Netherlands, Norway, Spain, Sweden, Switzerland
29	FINLAND HAYFORD 1910 - Finland
30	GANDAJIKA BASE - Republic of Maldives
31	GEODETIC DATUM 1949 - New Zealand
32	ORDNANCE SURVEY OF GREAT BRITAIN 1936 - England, Isle of Man, Scotland, Shetland Islands, Wales
33	GUAM 1963 - Guam Island
34	GUX 1 ASTRO - Guadalcanal Island
35	HJORSEY 1955 - Iceland
36	HONG KONG 1963 - Hong Kong
37	INDIAN - Bangladesh, India, Nepal
38	INDIAN - Thailand, Vietnam
39	IRELAND 1965 - Ireland
40	ISTS O73 ASTRO 1969 - Diego Garcia
41	JOHNSTON ISLAND 1961 - Johnston Island
42	KANDAWALA - Sri Lanka
43	KERGUELEN ISLAND - Kerguelen Island
44	KERTAUI 1948 - West Malaysia, Singapore
45	L.C. 5 ASTRO - Cayman Brac Island

46	LIBERIA 1964 - Liberia
47	LUZON - Mindanao Island
48	LUZON - Phillippines (excluding Mindanao Island)
49	MAHE 1971 - Mahe Island
50	MARCO ASTRO - Salvage Islands
51	MASSAWA - Eritrea (Ethiopia)
52	MERCHICH - Morocco
53	MIDWAY ASTRO 1961 - Midway Island
54	MINNA - Nigeria
55	NORTH AMERICAN 1927 - Alaska
56	NORTH AMERICAN 1927 - Bahamas (excluding San Salvador Island)
57	NORTH AMERICAN 1927 - Central America (Belize, Costa Rica, El Salvador, Guatemala, Honduras, Nicaragua)
58	NORTH AMERICAN 1927 - Canal Zone
59	NORTH AMERICAN 1927 - Canada (including Newfoundland Island)
60	NORTH AMERICAN 1927 - Caribbean (Barbados, Caicos Islands, Cuba, Dominican Republic, Grand Cayman, Jamaica, Leeward Islands, Turks Islands)
61	NORTH AMERICAN 1927 - Mean Value (CONUS)
62	NORTH AMERICAN 1927 - Cuba
63	NORTH AMERICAN 1927 - Greenland (Hayes Peninsula)
64	NORTH AMERICAN 1927 - Mexico
65	NORTH AMERICAN 1927 - San Salvador Island
66	NORTH AMERICAN 1983 - Alaska, Canada, Central America, CONUS, Mexico
67	NAPARIMA, BWI - Trinidad and Tobago
68	NAHRWAN - Masirah Island (Oman)
69	NAHRWAN - Saudi Arabia
70	NAHRWAN - United Arab Emirates
71	OBSERVATORIO 1966 - Corvo and Flores Islands (Azores)
72	OLD EGYPTIAN - Egypt
73	OLD HAWAIIAN - Mean Value
74	OMAN - Oman
75	PICO DE LAS NIEVES - Canary Islands
76	PITCAIRN ASTRO 1967 - Pitcairn Island
77	PUERTO RICO - Puerto Rico, Virgin Islands
78	QATAR NATIONAL - Qatar
79	QORNOQ - South Greenland
80	REUNION - Mascarene Island
81	ROME 1940 - Sardinia Island
82	RT 90 - Sweden
83	PROVISIONAL SOUTH AMERICAN 1956 - Bolivia, Chile, Colombia, Ecuador, Guyana, Peru, Venezuela
84	SOUTH AMERICAN 1969 - Argentina, Bolivia, Brazil, Chile, Colombia, Ecuador, Guyana, Paraguay, Peru, Venezuela, Trinidad and Tobago
85	SOUTH ASIA - Singapore
86	PROVISIONAL SOUTH CHILEAN 1963 - South Chile
87	SANTO (DOS) - Espirito Santo Island
88	SAO BRAZ - Sao Miguel, Santa Maria Islands (Azores)
89	SAPPER HILL 1943 - East Falkland Island
90	SCHWARZECK - Namibia
91	SOUTHEAST BASE - Porto Santo and Madeira Islands
92	SOUTHWEST BASE - Faial, Graciosa, Pico, Sao Jorge, and Terceira Islands (Azores)
93	TIMBALAI 1948 - Brunei and East Malaysia (Sarawak and Sabah)
94	TOKYO - Japan, Korea, Okinawa
95	TRISTAN ASTRO 1968 - Tristan da Cunha
96	User defined earth datum
97	VITI LEVU 1916 - Viti Levu Island (Fiji Islands)
98	WAKE-ENIWETOK 1960 - Marshall Islands
99	WORLD GEODETIC SYSTEM 1972

100 WORLD GEODETIC SYSTEM 1984
101 ZANDERIJ - Surinam
102 CH-1903 - Switzerland
103 Hu - Tzu - Shan
104 Indonesia 74
105 Austria
106 Potsdam
107 Taiwan - modified Hu-Tzu-Shan
108 GDA - Geocentric Datum of Australia
109 Dutch

Appendix B

Evaluation Software

The SNSRCFG Application

The configuration application **SNSRCFG** is available from the GARMIN web site (start at <http://www.garmin.com/oem>, select the product, and then select “Software Updates”). **SNSRCFG** will configure the GPS sensors based on user-selected parameters. Some application features include the ability to download GPS sensor configuration, maintain different configurations in files, and perform GPS sensor configurations quickly with the use of one function key. Online application help is available.

CAUTION

The GPSCFG application that was provided with earlier GARMIN GPS sensor board evaluation kits will put the GPS 16/17 series products in the Carrier Phase Output mode if default GPS 25/35 settings are used. This may be undesirable, as it disables the NMEA 0183 output format.

Appendix C

Binary Phase Output Format

NOTE

The following applies to GPS 17N software version 2.06 and higher, and all software versions of GPS 16-LVS, GPS 16-HVS, GPS 16A and GPS 17-HVS.

Two records are transmitted once per second by the GPS 16/17 series products. One record contains primarily post-process information such as position and velocity information. The second record contains receiver measurement information. The records are sent at a default baud rate of 9600 baud, 8 data bits, and no parity.

Records begin with a delimiter byte (10 hex). The second byte identifies the record type (33 hex for a position record, 34 hex for a receiver measurement). The third byte indicates the size of the data. The fourth byte is the first byte of data. The data is then followed by a checksum byte, a delimiter byte (10 hex), and an end-of-transmission character (03 hex).

Note - If RTCM-104 differential data is sent to the GPS sensor the board will reset the Phase Output Data baud rate to the same baud rate used for RTCM-104 data. If the differential inputs are used on the GPS sensor then the RTCM-104 data must be sent to the GPS sensor at 9600 baud (preferred) or 4800 baud. RTCM-104, baud rates less than 4800 baud are not supported by the GPS sensors since it would limit bus bandwidth past the point where a once per second phase output data rate could be maintained.

Position Record

- 0x10 (DLE is first byte)
- 0x33 (Position record identifier)
- 0x40 (Size of data)
- cpo_pvt_data (See description below)
- one-byte checksum (The addition of bytes between the delimiters should equal 0)
- 0x10 (DLE)
- 0x03 (ETX is last byte)

```
typedef struct
{
    float    alt;
    float    epe;
    float    eph;
    float    epv;
    int      fix;
    double   gps_tow;
    double   lat;
    double   lon;
    float    lon_vel;
    float    lat_vel;
    float    alt_vel;
    float    msl_hght;
    int      leap_sec;
    long     grmn_days;
} cpo_pvt_data;
```

alt	Ellipsoid altitude (meters)
epe	Est pos error (meters)
eph	Pos err, horizontal (meters)
epv	Pos err, vertical (meters)
fix	0 = no fix; 1 = no fix; 2 = 2D; 3 = 3D; 4 = 2D differential; 5 = 3D differential; 6 and greater - not defined
gps_tow	GPS time of week (sec)
lat	Latitude (radians)
lon	Longitude (radians)
lon_vel	Longitude velocity (meters/second)
lat_vel	Latitude velocity (meters/second)
alt_vel	Altitude velocity (meters/ second)
msl_hght	Mean sea level height (meters)
leap_sec	UTC leap seconds
grmn_days	GARMIN days (days since December 31, 1989)

Receiver Measurement Record

- 0x10	(DLE is first byte)
- 0x34	(Receiver record identifier)
- 0xE2	(Size of data)
- cpo_rcv_data	(See below)
- one byte checksum	(The sum of bytes between the delimiters should equal 0)
- 0x10	(DLE)
- 0x03	(ETX)

```
typedef struct
{
    unsigned long    cycles;
    double          pr;
    unsigned int    phase;
    char            slp_dtct;
    unsigned char   snr_dbhz;
    char            svid;
    char            valid;
} cpo_rcv_sv_data;
```

```
typedef struct
{
    double          rcvr_tow;
    int             rcvr_wn;
    cpo_rcv_sv_data sv[ 12 ];
} cpo_rcv_data;
```

rcvr_tow	Receiver time of week (seconds)
rcvr_wn	Receiver week number
cycles	Number of accumulated cycles
pr	Pseudorange (meters)
phase	To convert to (0 -359.999) multiply by 360.0 and divide by 2048.0
slp_dtct	0 = no cycle slip detected; non-zero = cycle slip detected
snr_dbhz	Signal strength
svid	Satellite number (0 - 31) Note - add 1 to offset to current svid numbers
valid	0 = information not valid; non-zero = information valid

DLE and ETX bytes:

Sample C code to receive the two records should filter DLE and ETX bytes as described below:

```
typedef enum
{
    DAT,
    DLE,
    ETX
} rx_state_type;

/* Declare and initialize static variables */
static char    in_que[ 256 ];
static int     in_que_ptr = 0;
static rx_state_type rx_state = DAT;

.
.
.

void add_to_que( char data )
{
#define DLE_BYTE 0x10
#define ETX_BYTE 0x03

if ( rx_state == DAT )
    {
        if ( data == DLE_BYTE )
            {
                rx_state = DLE;
            }
        else
            {
                in_que[ in_que_ptr++ ] = data;
            }
    }
else if ( rx_state == DLE )
    {
        if ( data == ETX_BYTE )
            {
                rx_state = ETX;
            }
        else
            {
                rx_state = DAT;
                in_que[ in_que_ptr++ ] = data;
            }
    }
else if ( rx_state == ETX )
    {
        if ( data == DLE_BYTE )
            {
                rx_state = DLE;
            }
    }

if ( in_que_ptr > 255 )
    {
        in_que_ptr = 0;
    }
}
```