



OXTS RT Multiple Target ADAS Measurement Solution User Guide

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RT Multiple Target ADAS Measurement Solution
User Guide



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Install

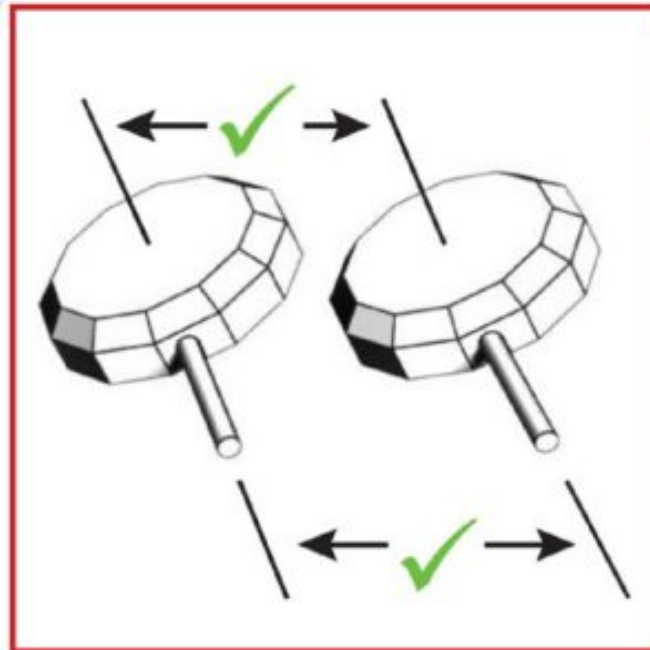
Mount the RT

We recommend using the RT-Strut (with the supplementary retaining strap system) in the centre of the rear footwells, or horizontally in the boot (trunk).



Position the antenna(s)

Mount the antenna(s) on the roof, at least 20 cm from the roof edge, or using the Dual Antenna Roof Mount. Make sure they are at least 1 m apart and the cables exit in the same direction.



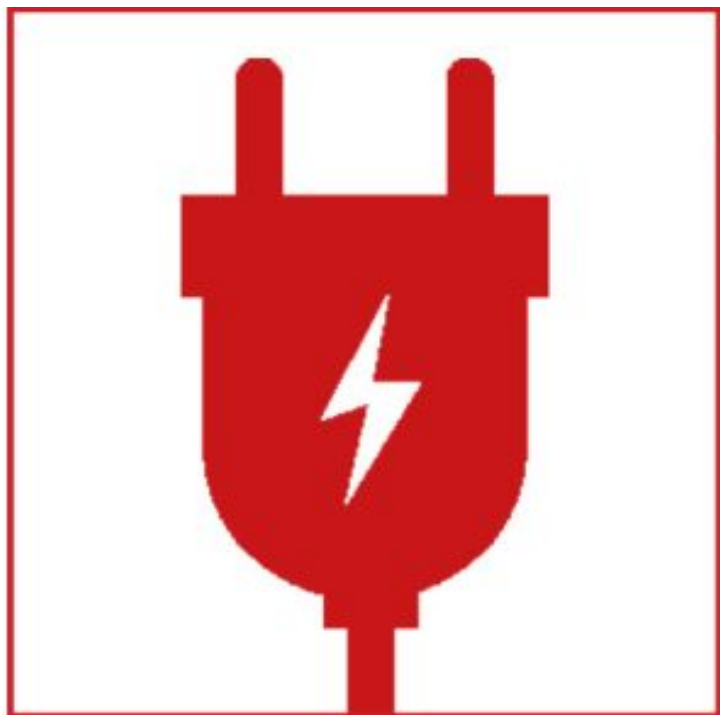
Connect the cables

Plug in the main user cable to the device and connect antenna cables. The primary antenna should be the one closest to the device.



Supply power

We recommend using a UPS or dedicated battery to supply power. Your device will then be visible in NAVsuite when trying to connect.



Setup IP connection to device

Ensure your PC's IP address settings enable you to connect via Ethernet, so you can move to configuration.



Configure

Open NAVconfig and select “New Configuration”

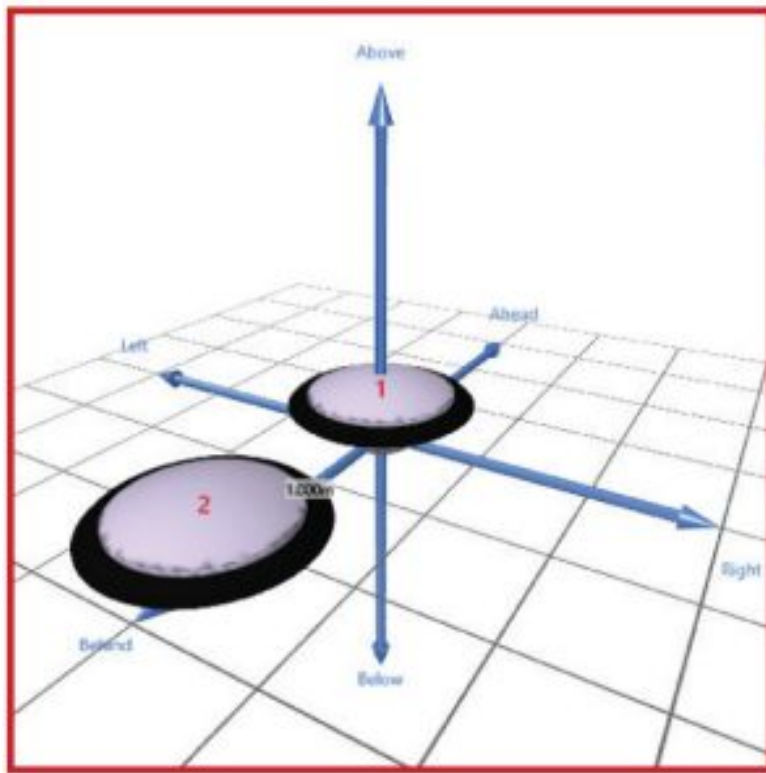


Read existing configuration or use default settings

Select your device and the type of vehicle.

IMU orientation

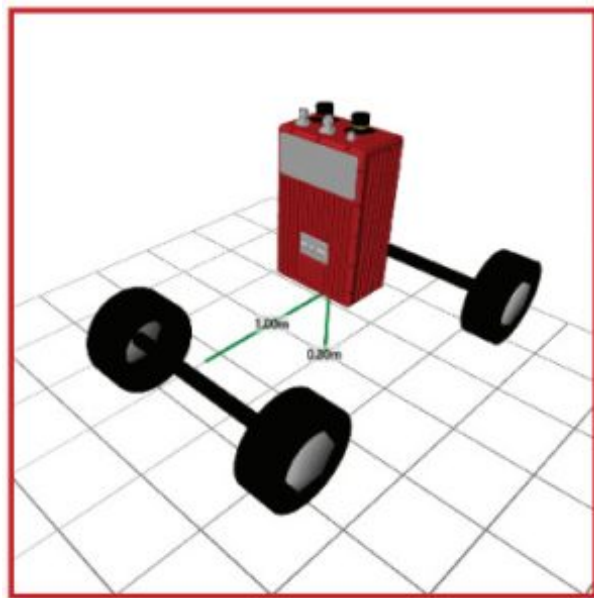
Set the Y&Z axes of the device within the vehicle.



Configure

Lateral and vertical no-slip

Input the distances of the steered and non-steered axles to the device.



GNSS corrections

Use the default settings, which work with our base stations, or change to match your own.

Hardware Setup
Position the device and the antennas, then input the requirements here.

Review the settings on this page and click Post when ready.

[B&B Information](#) | [Primary Antenna](#) | [Secondary Antenna](#) | [External No. dip](#) | [Vertical No. dip](#) | [GPRS Differential Corrections](#)

Configure GPRS differential corrections.

Correction format:

☐ Enable NTRIP
☐ Use internal client

Serial port settings (ask a modem):

Base Station datum:

Retransmit DGPS (NMEA):

GPRS:

Fixed star corrections:
 Latitude Selection:

 Longitude:

☐ Advanced settings

Modify 'Interface' settings

Configure your CAN output and acquisition settings, using CAN 2.0 or CAN-FD.

Interface
Configure the interface to use for your device.

Review the settings on this page and click Post when ready.

[Hardware Setup](#) | [CAN Output](#) | [CAN Acquisition](#) | [Serial Output](#) | [Serial Input](#) | [CAN Settings](#)

Configure settings for the interface.

☒ Enable CAN interface
☐ Use identifier as master/slave
☒ Enable CAN bus

CAN ID:

CAN speed:

CAN protocol:
☒ CAN 2.0
☐ CAN-FD

CAN bus termination:

CAN bus arbitration:

Configure CAN bus (Master/Slave) settings.

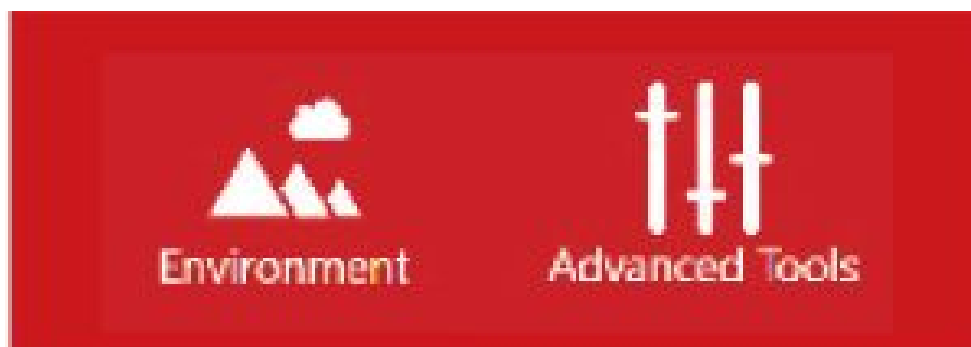
Function: [Setup](#)

Channel	Mode	Rate	Bit rate	Protocol	Comments
0	Master	1000	1000	CAN 2.0	Test and demo
1	Master/Slave	1000	1000	CAN 2.0	Master/Slave test
2	Master	1000	1000	CAN 2.0	Master
3	Master	1000	1000	CAN 2.0	CAN 2.0 Master
4	Master/Slave	1000	1000	CAN 2.0	CAN 2.0 Master/Slave

Speed: 1000, 1000, 1000, 1000, 1000, 1000, 1000, 1000

Use default settings

In the 'Environment' and 'Advanced Tools' for a quick start.



Write the configuration to your device

Select the correct IP for your unit and click commit. Once complete, save and finish your configuration.



Calibrate/Warm-up

Use the 'Warm up' template in NAVdisplay to help visualize your calibration

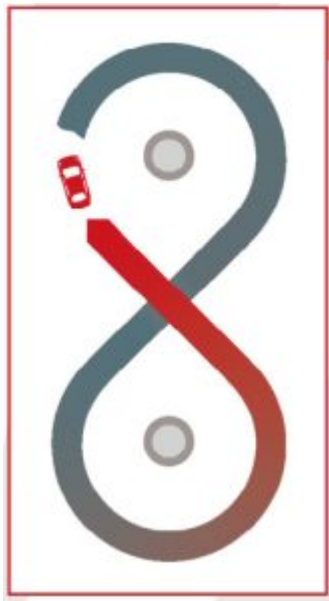
Initialize

Drive in a straight line, accelerating through the set initialization speed. The default is 5 m/s (18 km/h).



Figures of 8

Complete several figures of eight manoeuvres in your vehicle, braking into turns and accelerating out.



Decreasing circles

Drive in a circle at a fixed speed, and decrease the radius of your turns in both clockwise and anti-clockwise directions.



Slaloms

Complete a few slaloms, with short sharp turns.



Acceleration and braking

Apply hard acceleration and hard braking in a straight line, until at a complete stop (do not stall).



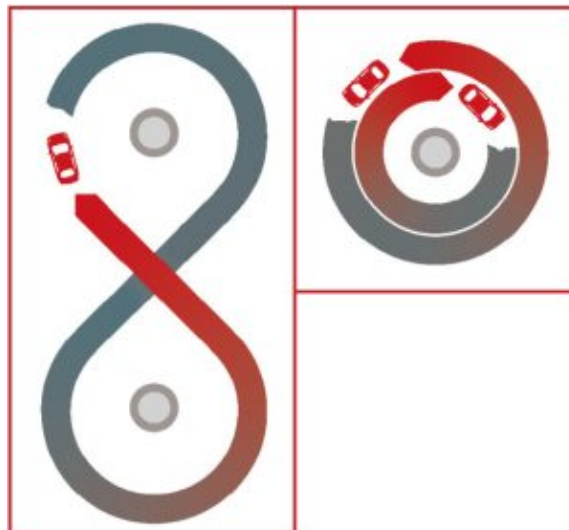
Commit settings to your device

Use NAVconfig and select “Improve Configuration” to apply the improved settings from your calibration to the device.



Re-initialize and complete quick warm-up

Repeat steps 2 and 3. Use NAVdisplay to check required performance level is reached.



Files are automatically saved internally from GPS start time, as YYYYMMDD_hhmmss.rd



Open NAVsolve and select your device

Select the desired file in preview

Process your file

Selecting whether you want simulated, forward, backward, or combined, amend other settings and click “Process”.

Export your data

Configure the file format for your desired output and click “Export”.

Need further assistance?



Go the support website: support.oxts.com

Or get in touch if you
can't find what you need:

support@oxts.com

+44(0)1869814251

Documents / Resources



[OXTS RT Multiple Target ADAS Measurement Solution](#) [pdf] User Guide

RT, Multiple Target, ADAS Measurement Solution, RT Multiple Target ADAS Measurement Solution