

PX1120DNP



GNSS Receiver with Dead Reckoning

Features

- 100% coverage
- Continuous position fix in tunnels
- Automatic sensor calibration
- 230 Channel receiver
- GPS/Beidou/GLONASS/QZSS/SBAS capable
- Perform 16 million time-frequency hypothesis testing per second
- Open sky hot start 1 sec
- Open sky cold start 29 sec
- Accuracy 2.5m CEP
- Operating temperature -40 ~ +85°C
- RoHS compliant

Applications

- Automotive Navigation

The PX1120DNP GNSS Dead-Reckoning receiver module combines GNSS position data, gyroscope data (measuring turning angle), and optional odometer data (measuring distance traveled) to formulate position solution. This enables accurate navigation solution in poor signal environment or signal blocked area such as inside tunnels. The PX1120DNP is ideal for 4-wheel vehicle applications requiring accurate continuous navigation with 100% availability.

PX1120DNP can operate in Automotive Dead Reckoning (**ADR**) mode if the vehicle wheel-tick odometer signal is connected; or operate in Odometer-less Dead Reckoning (**ODR**) mode if the odometer signal is not connected.

The Extended Kalman Filter algorithm combines GNSS and sensor data with weighting function dependent on GNSS signal quality. In poor signal reception area and multipath environment, the position error is reduced by dead reckoning.

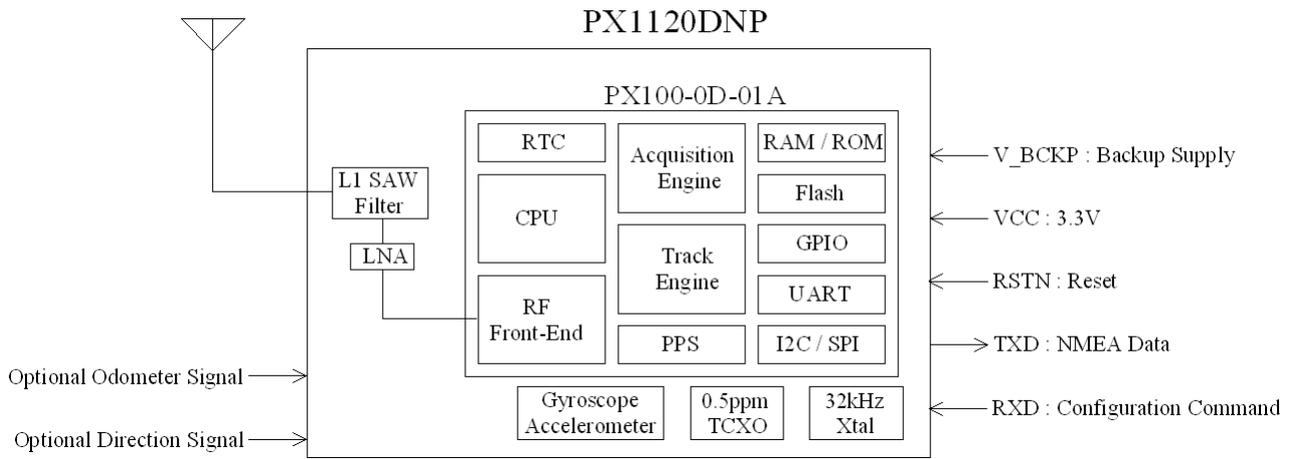
The PX1120DNP with dead-reckoning feature, position is output as soon as power is applied to the module without the need of getting GPS/GNSS position fix.

The receiver is suitable for navigation and tracking systems that require high performance continuous positioning and velocity data.

TECHNICAL SPECIFICATIONS

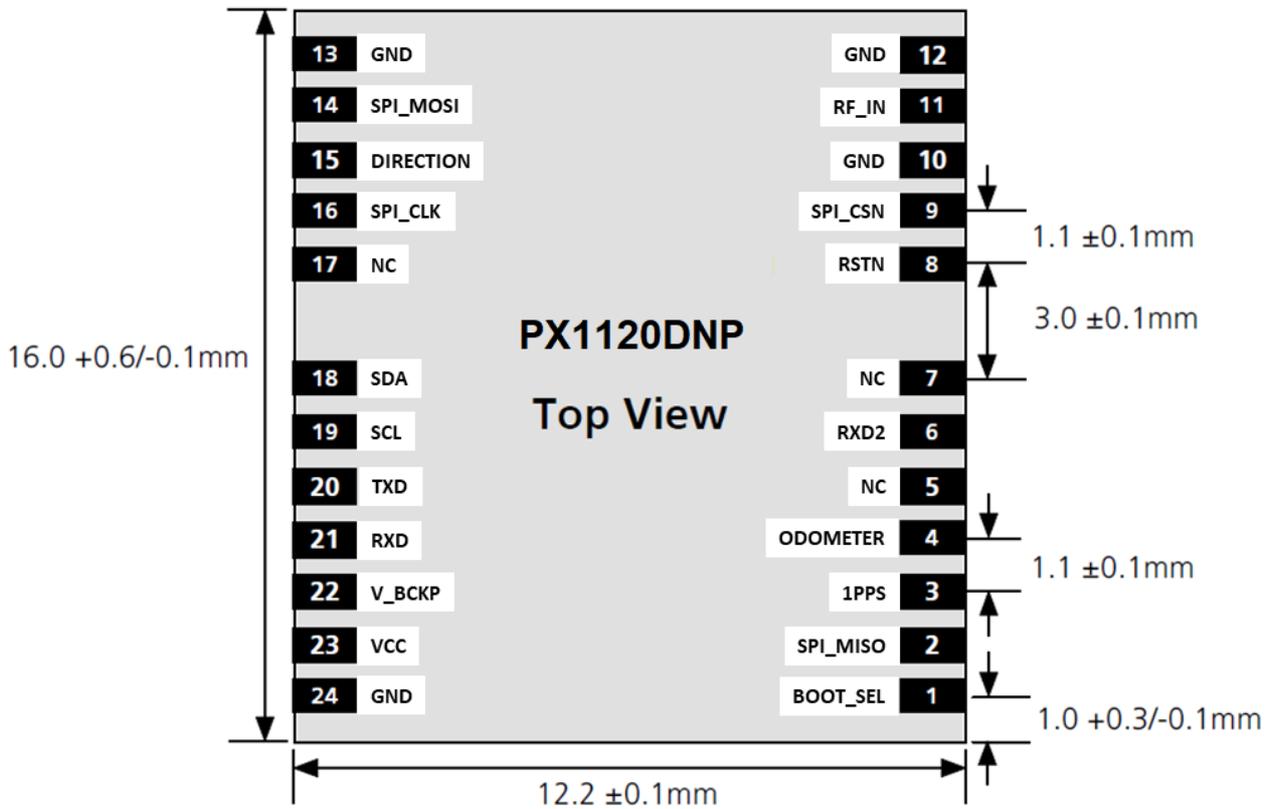
Receiver Type	230-channel PHOENIX engine L1 GPS/QZSS/SBAS, B1 Beidou, L1 GLONASS capable
Accuracy	Position 2.5m CEP Velocity 0.1m/sec Time 12ns
Startup Time	1 second hot start under open sky 28 second warm-start under open sky (average) 29 second cold-start under open sky (average)
Reacquisition	1s
Sensitivity	-148dBm cold start -165dBm tracking
Update Rate	1 / 2 / 4 / 8 / 10 Hz
Operational Limits	Altitude < 18,000m and velocity < 515m/s
Serial Interface	3.3V LVTTTL level
Protocol	NMEA-0183 V3.01 SkyTraq Binary 38400 baud, 8, N, 1
Datum	Default WGS-84 User definable
Input Voltage	3.3V+/- 10%
Input Current	Acquisition 85mA @ 3.3V, Tracking 75mA @ 3.3V
Dimension	16.0mm L x 12.2mm W x 2.9mm H
Weight:	2g
Operating Temperature	-40°C ~ +85°C
Storage Temperature	-55 ~ +100°C
Humidity	5% ~ 95%

BLOCK DIAGRAM



Module block schematic

INTERFACE

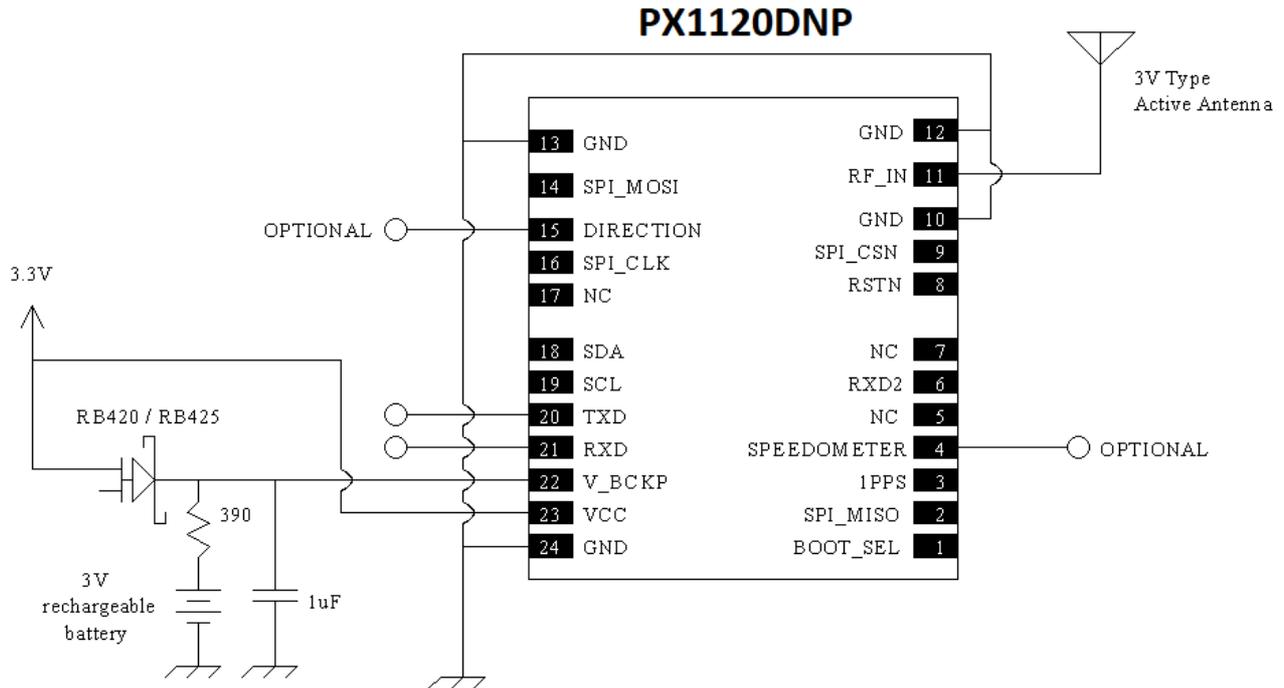


PINOUT DESCRIPTION

Pin No.	Name	Description
1	BOOT_SEL	No connection for normal use. Pull-low for loading firmware into empty or corrupted Flash memory from ROM mode.
2	SPI_MISO	No connection for normal use.
3	1PPS	One-pulse-per-second (1PPS) time mark output, 3V LVTTL. The rising edge synchronized to UTC second when getting 3D position fix. The pulse duration is 100msec at rate of 1 Hz.
4	ODOMETER	Optional car speed pulse input, frequency < 4kHz.
5	NC	No connection
6	RXD2	No connection for normal use.
7	NC	No connection
8	RSTN	External reset (active low). Can be left unconnected if unused.
9	SPI_CSN	No connection for normal use.
10	GND	Ground
11	RF_IN	RF input with 3.3V active antenna bias voltage
12	GND	Ground
13	GND	Ground
14	SPI_MOSI	No connection for normal use.

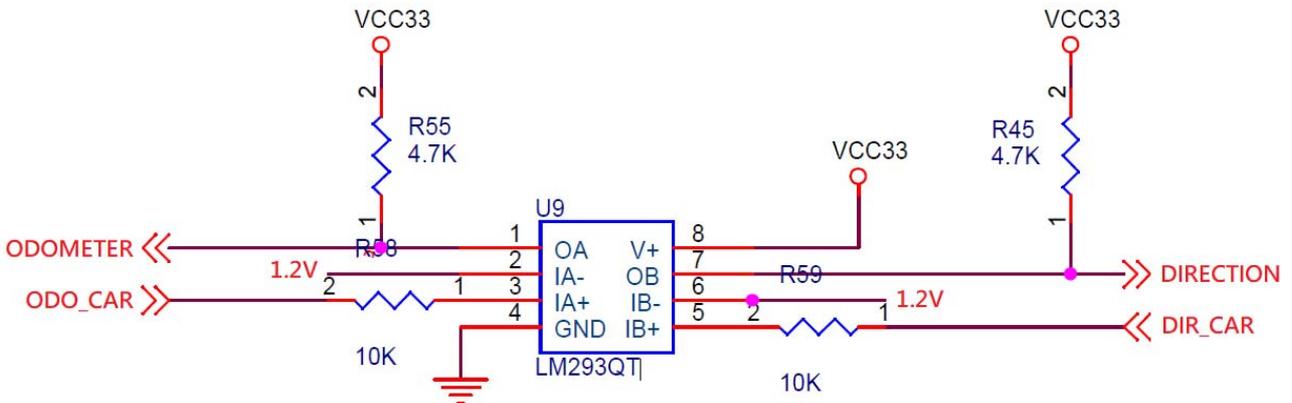
15	DIRECTION	Optional forward (LOW) or reverse direction (HIGH) input from vehicle.
16	SPI_CLK	No connection for normal use.
17	NC	No connection
18	SDA	No connection for normal use.
19	SCL	No connection for normal use.
20	TXD	1 st UART serial data output, 3.3V LVTTTL. This UART output is normally used for sending position, time and velocity information from the receiver in NMEA-0183 format. When idle, this pin output HIGH.
21	RXD	1 st UART serial data input, 3.3V LVTTTL. This UART input is normally for sending commands or information to the receiver in SkyTraq binary protocol. In the idle condition, this pin should be driven HIGH. If the driving circuitry is powered independently of PX1120DNP, ensure that this pin is not driven to HIGH when primary power to PX1120DNP is removed.
22	V_BCKP	Backup supply voltage for internal RTC and backup SRAM, 1.3V ~ 3.6V. V_BCKP must be applied whenever VCC is applied. This pin should be powered continuously to minimize the startup time and for keeping DR calibration data. If VCC and V_BCKP are both removed, the receiver will be in factory default mode upon power up, all user configuration and calibrated DR parameters are lost.
23	VCC	Main 3.3V DC supply input
24	GND	Digital ground

APPLICATION CIRCUIT



Automotive Dead-Reckoning (ADR)

For ADR type of application where vehicle odometer wheel-tick pulse signal is available, connect pin-4 ODOMETER to the wheel-tick signal through appropriate level shifter such that the wheel-tick signal level is within range of LVTTTL (0V ~ 3.3V). Similarly connect pin-15 DIRECTION to the vehicle forward/reverse signal. For ADR applications that has no forward/reverse indication signal, simply ground the DIRECTION input. Below is a level shifter example circuitry.

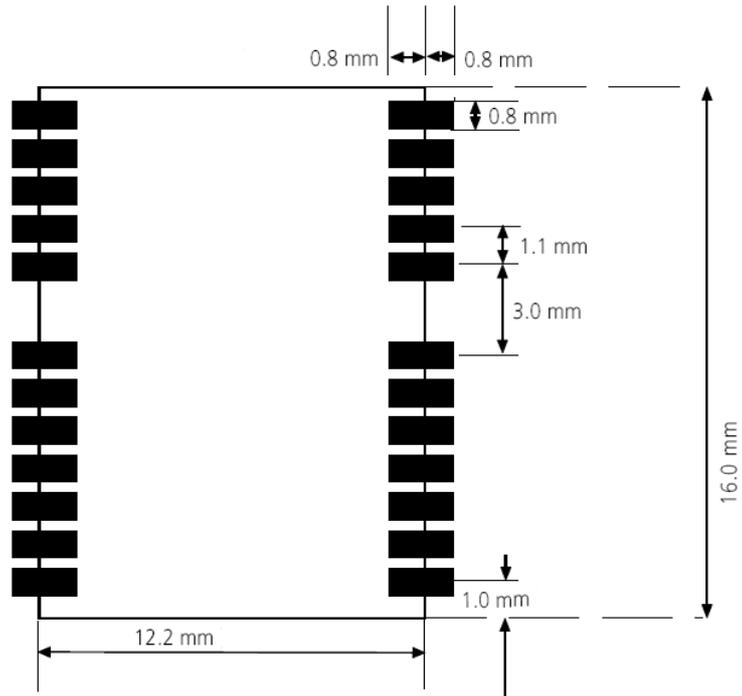


Odometer-less Dead-Reckoning (ODR)

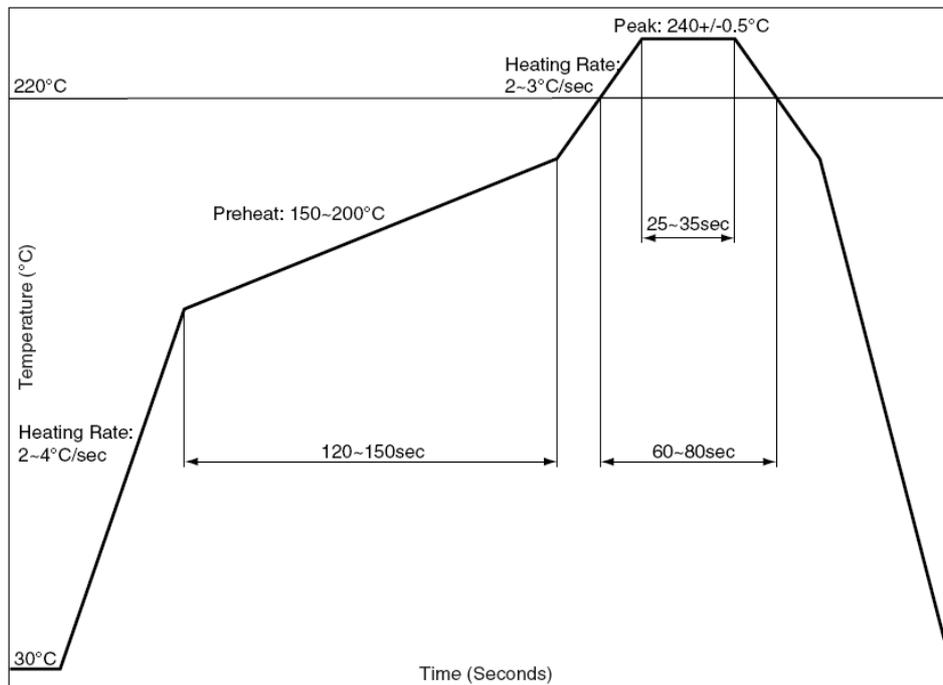
If the vehicle odometer wheel-tick pulse signal is not available, then PX1120DNP can operate in odometer-less dead-reckoning mode without the need of external connection to ODOMETER and DIRECTION pins.

When changing between ADR and ODR mode of operation, cold start command should be issued, or the V_BCKP power should be removed such that internal DR state will be cleared and PX1120DNP will re-do DR calibration.

RECOMMENDED FOOTPRINT



RECOMMENDED REFLOW PROFILE



The reflow profile shown above should not be exceeded, since excessive temperatures or transport times during reflow can damage the module. Cooling temperature fall rate: max 3°C / sec

ELECTRICAL SPECIFICATIONS

ABSOLUTE MAXIMUM RATINGS

Parameter	Minimum	Maximum	Condition
Supply Voltage (VCC)	-0.5	3.6	Volt
Backup Battery Voltage (V_BCKP)	-0.5	3.6	Volt
Input Pin Voltage	-0.5	VCC+0.5	Volt
Input Power at RF_IN		+5	dBm
Storage Temperature	-55	+100	degC

OPERATING CONDITIONS

Parameter	Min	Typ	Max	Unit
Supply Voltage (VCC)	3.0	3.3	3.6	Volt
Supply Current (exclude active antenna current)		85		mA
Backup Voltage (V_BCKP)	1.3		3.6	Volt
Backup Current (VCC voltage applied)		54		uA
Backup Current (VCC voltage off)		13		uA
Output Low Voltage			0.4	Volt
Output HIGH Voltage	2.4			Volt
Input LOW Voltage			0.8	Volt
Input HIGH Voltage	2			Volt
Input LOW Current	-10		10	uA
Input HIGH Current	-10		10	uA
RF Input Impedance (RF_IN)		50		Ohm

POWER SUPPLY REQUIREMENT

PX1120DNP requires a stable power supply, avoid ripple on VCC pin (<50mVpp). Power supply noise can affect the receiver's sensitivity. Bypass capacitors should be placed close to the module VCC pin, with values adjusted depending on the amount and type of noise present on the supply line.

BACKUP SUPPLY

The purpose of backup supply voltage pin (V_BCKP) is to keep the SRAM memory and the RTC powered when the module is powered down. This enables the module to have a faster time-to-first-fix when the module is powered on again. DR calibration data is also kept in this SRAM. If V_BCKP is not maintained when main power is removed, the receiver will need to go through auto calibration process before DR could take effect every time it's powered on. The backup current drain is less than 35 μ A. In normal powered on state, the internal processor access the SRAM and current drain is higher in active mode

ANTENNA CONSIDERATION

3.3V GPS/GLONASS or GPS/Beidou active antenna with 10dB ~ 20dB gain and noise figure less than 2dB can be used for better performance.

CALIBRATION of DR

PX1120DNP performs calibration of gyro bias and odometer scale automatically using GNSS. Customer is not required to perform calibration at installation.

For product testing or benchmarking, the following procedure steps can achieve efficient calibration quickly after a short period of time:

1. Find a open sky place.
2. Start PX1120DNP and stand still for 60 seconds until position fix is achieved.
3. Drive straight for 500m at speed of at least 40km/hr.
4. For next 3 minutes, drive straight and make at least 360-deg turns (either two 90-degrees left turns and right turns, or four left turns, or four right turns) then drive straight for at least another 300m.

NMEA Output Description

The output protocol supports NMEA-0183 standard. The implemented messages include GGA, GLL, GSA, GSV, VTG, RMC, ZDA and GNS messages. The NMEA message output has the following sentence structure:

```
$aacc,c-c*hh<CR><LF>
```

The detail of the sentence structure is explained in Table 1.

Table 1: The NMEA sentence structure

character	HEX	Description
"\$"	24	<u>Start of sentence.</u>
Aacc		<u>Address field.</u> "aa" is the talker identifier. "ccc" identifies the sentence type.
","	2C	<u>Field delimiter.</u>
c-c		<u>Data sentence block.</u>
"*"	2A	<u>Checksum delimiter.</u>
Hh		<u>Checksum field.</u>
<CR><LF>	0D0A	<u>Ending of sentence.</u> (carriage return, line feed)

Table 2: Overview of SkyTraq receiver's NMEA messages for PX1120DNP with GPS/Beidou/DR firmware

\$GNGGA	Time, position, and fix related data of the receiver.
\$GNGLL	Position, time and fix status.
\$GNGSA \$GPGSA \$BDGSA	Used to represent the ID's of satellites which are used for position fix. When both GPS and Beidou satellites are used in position solution, a \$GNGSA sentence is used for GPS satellites and another \$GNGSA sentence is used for Beidou satellites. When only GPS satellites are used for position fix, a single \$GPGSA sentence is output. When only Beidou satellites are used, a single \$BDGSA sentence is output.
\$GPGSV \$BDGSV	Satellite information about elevation, azimuth and CNR, \$GPGSV is used for GPS satellites, while \$BDGSV is used for Beidou satellites
\$GNRMC	Time, date, position, course and speed data.
\$GNVTG	Course and speed relative to the ground.
\$GNZDA	UTC, day, month and year and time zone.

Table 3: Overview of SkyTraq receiver's NMEA messages for PX1120DNP with GPS/GLONASS/DR firmware

\$GNGGA	Time, position, and fix related data of the receiver.
\$GNGLL	Position, time and fix status.
\$GNGSA \$GPGSA \$GLGSA	Used to represent the ID's of satellites which are used for position fix. When both GPS and GLONASS satellites are used in position solution, a \$GNGSA sentence is used for GPS satellites and another \$GNGSA sentence is used for GLONASS satellites. When only GPS satellites are used for position fix, a single \$GPGSA sentence is output. When only GLONASS satellites are used, a single \$GLGSA sentence is output.
\$GPGSV \$GLGSV	Satellite information about elevation, azimuth and CNR, \$GPGSV is used for GPS satellites, while \$GLGSV is used for GLONASS satellites
\$GNRMC	Time, date, position, course and speed data.
\$GNVTG	Course and speed relative to the ground.
\$GNZDA	UTC, day, month and year and time zone.

The formats of the supported NMEA messages are described as follows:

GGA - Global Positioning System Fix Data

Time, position and fix related data for a GPS receiver.

Structure:

\$GPGGA,hhmmss.sss,ddmm.mmmm,a,dddmm.mmmm,a,x,xx,x.x,x.x,M,,,,,xxxx*hh<CR><LF>
 1 2 3 4 5 6 7 8 9 10 11

Example:

\$GPGGA,111636.932,2447.0949,N,12100.5223,E,1,11,0.8,118.2,M,,,,,0000*02<CR><LF>

Field	Name	Example	Description
1	UTC Time	111636.932	UTC of position in hhmmss.sss format, (000000.000 ~ 235959.999)
2	Latitude	2447.0949	Latitude in ddmm.mmmm format Leading zeros transmitted
3	N/S Indicator	N	Latitude hemisphere indicator, 'N' = North, 'S' = South
4	Longitude	12100.5223	Longitude in dddmm.mmmm format Leading zeros transmitted
5	E/W Indicator	E	Longitude hemisphere indicator, 'E' = East, 'W' = West
6	GPS quality indicator	1	GPS quality indicator 0: position fix unavailable 1: valid position fix, SPS mode 2: valid position fix, differential GPS mode 3: GPS PPS Mode, fix valid 4: Real Time Kinematic. System used in RTK mode with fixed integers 5: Float RTK. Satellite system used in RTK mode. Floating integers 6: Estimated (dead reckoning) Mode 7: Manual Input Mode 8: Simulator Mode
7	Satellites Used	11	Number of satellites in use, (00 ~ 28)
8	HDOP	0.8	Horizontal dilution of precision, (00.0 ~ 99.9)
9	Altitude	108.2	mean sea level (geoid), (-9999.9 ~ 17999.9)
10	DGPS Station ID	0000	Differential reference station ID, 0000 ~ 1023 NULL when DGPS not used
11	Checksum	02	

GLL – Latitude/Longitude

Latitude and longitude of current position, time, and status.

Structure:

\$GPGLL,ddmm.mmmm,a,dddmm.mmmm,a,hhmmss.sss,A,a*hh<CR><LF>
 1 2 3 4 5 6 7 8

Example:

\$GPGLL,2447.0944,N,12100.5213,E,112609.932,A,A*57<CR><LF>

Field	Name	Example	Description
1	Latitude	2447.0944	Latitude in ddmm.mmmm format Leading zeros transmitted
2	N/S Indicator	N	Latitude hemisphere indicator 'N' = North 'S' = South
3	Longitude	12100.5213	Longitude in dddmm.mmmm format Leading zeros transmitted
4	E/W Indicator	E	Longitude hemisphere indicator 'E' = East 'W' = West
5	UTC Time	112609.932	UTC time in hhmmss.sss format (000000.000 ~ 235959.999)
6	Status	A	Status, 'A' = Data valid, 'V' = Data not valid
7	Mode Indicator	A	Mode indicator 'N' = Data not valid 'A' = Autonomous mode 'D' = Differential mode 'E' = Estimated (dead reckoning) mode 'M' = Manual input mode 'S' = Simulator mode
8	Checksum	57	

GSA – GNSS DOP and Active Satellites

GPS receiver operating mode, satellites used in the navigation solution reported by the GGA or GNS sentence and DOP values.

Structure:

```
$GPGSA,A,x,xx,xx,xx,xx,xx,xx,xx,xx,xx,xx,xx,xx,x.x,x.x,x.x*hh<CR><LF>
  1 2 3 3 3 3 3 3 3 3 3 3 3 4 5 6 7
```

Example:

```
$GPGSA,A,3,05,12,21,22,30,09,18,06,14,01,31,,1.2,0.8,0.9*36<CR><LF>
```

Field	Name	Example	Description
1	Mode	A	Mode 'M' = Manual, forced to operate in 2D or 3D mode 'A' = Automatic, allowed to automatically switch 2D/3D
2	Mode	3	Fix type 1 = Fix not available 2 = 2D 3 = 3D
3	Satellite used 1~12	05,12,21,22,30,09,18,06,14,01,31,,	01 ~ 32 are for GPS; 33 ~ 64 are for WAAS (PRN minus 87); 65 ~ 96 are for GLONASS (64 plus slot numbers); 193 ~ 197 are for QZSS; 01 ~ 37 are for Beidou (BD PRN). GPS and Beidou satellites are differentiated by the GP and BD prefix. Maximally 12 satellites are included in each GSA sentence.
4	PDOP	1.2	Position dilution of precision (00.0 to 99.9)
5	HDOP	0.8	Horizontal dilution of precision (00.0 to 99.9)
6	VDOP	0.9	Vertical dilution of precision (00.0 to 99.9)
7	Checksum	36	

GSV – GNSS Satellites in View

Number of satellites (SV) in view, satellite ID numbers, elevation, azimuth, and SNR value. Four satellites maximum per transmission.

Structure:

```
$GPGSV,x,x,xx,xx,xx,xxx,xx,...,xx,xx,xxx,xx *hh<CR><LF>
    1 2 3 4 5 6 7    4 5 6 7 8
```

Example:

```
$GPGSV,3,1,12,05,54,069,45,12,44,061,44,21,07,184,46,22,78,289,47*72<CR><LF>
$GPGSV,3,2,12,30,65,118,45,09,12,047,37,18,62,157,47,06,08,144,45*7C<CR><LF>
$GPGSV,3,3,12,14,39,330,42,01,06,299,38,31,30,256,44,32,36,320,47*7B<CR><LF>
```

Field	Name	Example	Description
1	Number of message	3	Total number of GSV messages to be transmitted (1-5)
2	Sequence number	1	Sequence number of current GSV message
3	Satellites in view	12	Total number of satellites in view (00 ~ 20)
4	Satellite ID	05	01 ~ 32 are for GPS; 33 ~ 64 are for WAAS (PRN minus 87); 65 ~ 96 are for GLONASS (64 plus slot numbers); 193 ~ 197 are for QZSS; 01 ~ 37 are for Beidou (BD PRN). GPS and Beidou satellites are differentiated by the GP and BD prefix. Maximally 4 satellites are included in each GSV sentence.
5	Elevation	54	Satellite elevation in degrees, (00 ~ 90)
6	Azimuth	069	Satellite azimuth angle in degrees, (000 ~ 359)
7	SNR	45	C/No in dB (00 ~ 99) Null when not tracking
8	Checksum	72	

RMC – Recommended Minimum Specific GNSS Data

Time, date, position, course and speed data provided by a GNSS navigation receiver.

Structure:

\$GPRMC,hhmmss.sss,A,dddmm.mmmm,a,dddmm.mmmm,a,x.x,x.x,ddmmyy,,,a*hh<CR><LF>
 1 2 3 4 5 6 7 8 9 10 11

Example:

\$GPRMC,111636.932,A,2447.0949,N,12100.5223,E,000.0,000.0,030407,,,A*61<CR><LF>

Field	Name	Example	Description
1	UTC time	0111636.932	UTC time in hhmmss.sss format (000000.000 ~ 235959.999)
2	Status	A	Status 'V' = Navigation receiver warning 'A' = Data Valid
3	Latitude	2447.0949	Latitude in dddmm.mmmm format Leading zeros transmitted
4	N/S indicator	N	Latitude hemisphere indicator 'N' = North 'S' = South
5	Longitude	12100.5223	Longitude in dddmm.mmmm format Leading zeros transmitted
6	E/W Indicator	E	Longitude hemisphere indicator 'E' = East 'W' = West
7	Speed over ground	000.0	Speed over ground in knots (000.0 ~ 999.9)
8	Course over ground	000.0	Course over ground in degrees (000.0 ~ 359.9)
9	UTC Date	030407	UTC date of position fix, ddmmyy format
10	Mode indicator	A	Mode indicator 'N' = Data not valid 'A' = Autonomous mode 'D' = Differential mode 'E' = Estimated (dead reckoning) mode 'M' = Manual input mode 'S' = Simulator mode
11	checksum	61	

VTG – Course Over Ground and Ground Speed

The Actual course and speed relative to the ground.

Structure:

GPVTG,x.x,T,,M,x.x,N,x.x,K,a*hh<CR><LF>
1 2 3 4 5

Example:

\$GPVTG, 000.0,T,,M,000.0,N,0000.0,K,A*3D<CR><LF>

Field	Name	Example	Description
1	Course	000.0	True course over ground in degrees (000.0 ~ 359.9)
2	Speed	000.0	Speed over ground in knots (000.0 ~ 999.9)
3	Speed	0000.0	Speed over ground in kilometers per hour (0000.0 ~ 1800.0)
4	Mode	A	Mode indicator 'N' = not valid 'A' = Autonomous mode 'D' = Differential mode 'E' = Estimated (dead reckoning) mode 'M' = Manual input mode 'S' = Simulator mode
5	Checksum	3D	

STI,20 Dead Reckoning Status message

Structure:

PSTI,xx,x,x,x,xx,x,x,x,xxx.xx,xx.xx,xx.xx,x.xx*xx<CR><LF>
 1 2 3 4 5 6 7 8 9 10 11 12 13

Example:

\$PSTI,20,1,1,1,32,A,0,1,821.95,20.73,-13.45,6.63*40<CR><LF>

Field No.	Example	Format	Unit	Description
1	20	numeric	-	Proprietary message identifier: 20
2	1	numeric	-	DR Calibration Status 1: calibrated 0: not calibrated
3	1	numeric	-	Gyro Calibrate Status 1: calibrated 0: not calibrated
4	1	numeric	-	Sensor input available 1: available 0: not available
5	32	numeric	Pulse	ADR: odometer pulse count ODR: 0
6	A	character	-	Position Mode indicator: A=GPS fix, N = Data not valid, E = Estimated(dead reckoning) mode
7	0	numeric	-	Backward Status ADR 1: activated, moving backward 0: normal, moving forward ODR 0
8	1	numeric	-	Antenna detection (Reserved) 1: antenna available 0: antenna not available
9	821.95	numeric	0.002V	Z-axis gyro bias
10	20.73	numeric	cm/pulse	ADR: odometer scaling factor ODR: 100
11	-13.45	numeric	Deg/sec	Z-axis rotation rate
12	6.63	numeric	m	ADR: distance moved per second ODR: 0
13	40	hexadecimal	-	Checksum

ORDERING INFORMATION

Model Name	Description
PX1120DNP-BD	GNSS Dead Reckoning Receiver Module, GPS/Beidou Version
PX1120DNP-GL	GNSS Dead Reckoning Receiver Module, GPS/GLONASS Version

Revision History

Revision	Date	Description
1	April 9, 2021	Initial release

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