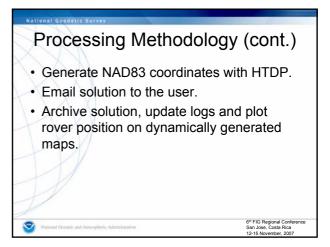
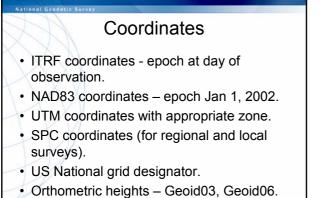
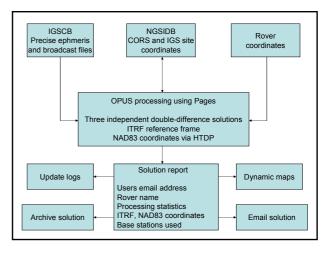


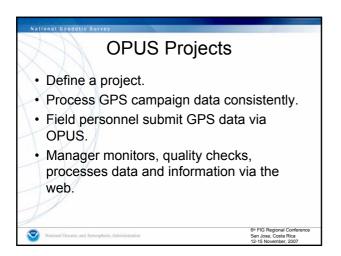


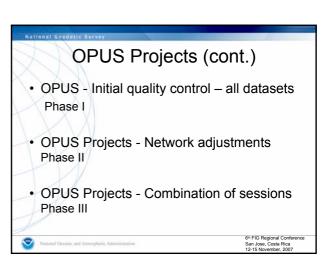
# Processing Methodology Compute rover (user's receiver) location. Retrieve ancillary information. Broadcast and precise ephemeris files from IGS Central Bureau. CORS and IGS site coordinates from NGSIDB. Performs three independent double-difference solutions within the ITRF reference frame. Compare and average the results.

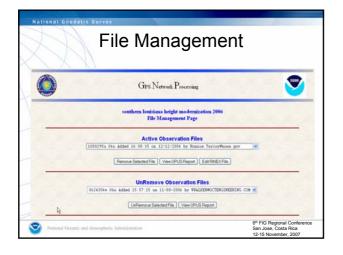


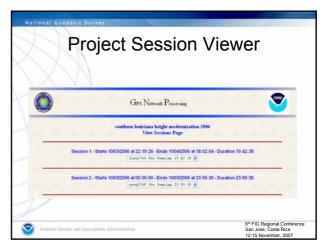


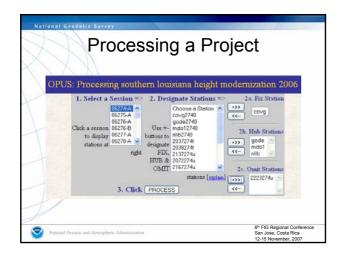


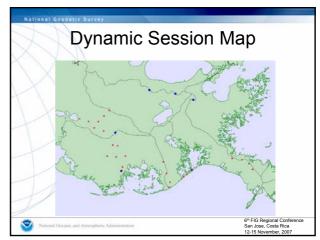












### OPUS-RS OPUS Rapid Static

- OPUS-RS uses RSGPS engine (from OSU) instead of Pages.
- Uses P1 and P2 as well as L1 and L2 observations.
- Resolves all ambiguities with LAMBDA.
- Geometry free linear combination used to determine DD ionospheric delays.



## **OPUS-RS Operational Modes**

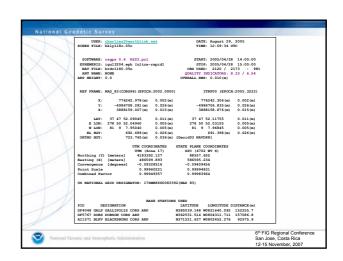
- May be used in two modes:
   Network and Rover
- In network mode, only reference stations are used to solve for ambiguities and double difference ionospheric delays.
- In rover mode, ionospheric delays and tropospheric parameters are interpolated from reference stations to rover.



# OPUS-RS Performance

- Produces a solution with 15 minutes of data (vs. 2 hours for OPUS).
- Network solution rather than individual baselines.
- Accuracy: 2 cm horizontal, 4 cm vertical.
- Quality indicators based on W ratio from LAMBDA validation tests.





### **Desired OPUS Features**

- Process multiple files from users as a network.
- Process single frequency (L1) data.
- Publish OPUS results in a database for external user access.
- Reduce occupation time.



