




TM Series GNSS Receiver Module Data Guide

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TM Series GNSS Receiver

Data Guide



Description

The TM Series GNSS receiver module is a self-contained high-performance Global Satellite Navigation System receiver. Based on the MediaTek chipset, it can simultaneously acquire and track multiple satellite constellations. These include the United States GPS system, Europe's GALILEO, Russia's GLONASS and Japan's QZSS.

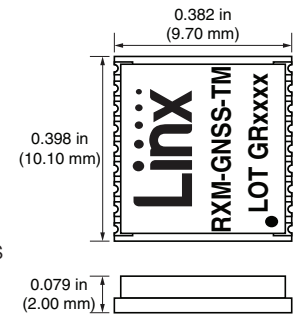


Figure 1: Package Dimensions

The module has an internal Low Noise Amplifier (LNA) that provides exceptional sensitivity, even in dense foliage and urban canyons. It's very low power consumption helps maximize runtimes in battery powered applications. Hybrid ephemeris prediction can be used to achieve cold start times of less than 15 seconds. The module outputs standard NMEA data through a UART interface.

Housed in a tiny reflow-compatible SMD package, the receiver requires no programming or additional RF components (except an antenna) to form a complete GNSS solution. This makes the TM Series easy to integrate, even by engineers without previous RF or GNSS experience.

Features

- MediaTek chipset
- High sensitivity (-164dBm)
- Fast TTFF at low signal levels
- Battery-backed SRAM
- 3-day ephemeris prediction
- No programming necessary
- No external RF components needed (except an antenna)
- No production tuning
- UART serial interface
- Power control features
- Compact SMD package

Applications Include

- Positioning and Navigation
- Location and Tracking
- Security/Loss-Prevention
- Surveying
- Logistics
- Fleet Management

Ordering Information

| Ordering Information | |
|--------------------------------------------------------|---------------------------------------------------|
| Part Number | Description |
| RXM-GNSS-TM-x | TM Series GNSS Receiver Module |
| MDEV-GNSS-TM | TM Series GNSS Receiver Master Development System |
| EVM-GNSS-TM | TM Series Evaluation Module |
| x = "T" for Tape and Reel, "B" for Bulk | |
| Reels are 1,500 pieces | |
| Quantities less than 1,500 pieces are supplied in bulk | |

Figure 2: Ordering Information

Absolute Maximum Ratings

| Absolute Maximum Ratings | | | | |
|--------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|------|----|-----|-----|
| Supply Voltage V_{CC} | +4.3 | | | VDC |
| Input Battery Backup Voltage | +4.3 | | | VDC |
| VCC_RF Output Current | 50 | | | mA |
| Operating Temperature | -40 | to | +85 | °C |
| Storage Temperature | -40 | to | +85 | °C |
| Exceeding any of the limits of this section may lead to permanent damage to the device. Furthermore, extended operation at these maximum ratings may reduce the life of this device. | | | | |

Figure 3: Absolute Maximum Ratings

Electrical Specifications

| TM Series GNSS Receiver Specifications | | | | | | |
|----------------------------------------|-----------|------|-------|------|-------|-------|
| Parameter | Symbol | Min. | Typ. | Max. | Units | Notes |
| Power Supply | | | | | | |
| Operating Voltage | V_{CC} | 3.0 | 3.3 | 4.3 | VDC | |
| Supply Current | I_{CC} | | | | | |
| Peak | | | | 156 | mA | 1 |
| Acquisition | | | 28 | | mA | 1 |
| Tracking | | | 20 | | mA | 1 |
| Standby | | | 0.365 | | mA | 1 |
| Backup Battery Voltage | V_{BAT} | 2.0 | | 4.3 | VDC | |
| Backup Battery Current | I_{BAT} | | 7 | | μA | 2 |

| TM Series GNSS Receiver Specifications | | | | | | |
|--------------------------------------------------------------------------------|-------------------------------------------------------------------------------------------------|------|------|--------|-------|-------|
| Parameter | Symbol | Min. | Typ. | Max. | Units | Notes |
| VOUT Output Voltage | V _{OUT} | 2.7 | 2.8 | 2.9 | VDC | |
| VOUT Output Current | I _{OUT} | | | 30 | mA | 1 |
| Output Low Voltage | V _{OL} | | | 0.4 | VDC | |
| Output High Voltage | V _{OH} | 2.4 | | 3.3 | | |
| Output Low Current | I _{OL} | | 2.0 | | mA | |
| Output High Current | I _{OH} | | 2.0 | | mA | |
| Input Low Voltage | V _{IL} | −0.3 | | 0.8 | VDC | |
| Input High Voltage | V _{IH} | 2.0 | | 3.6 | VDC | |
| Input Low Current | V _{IL} | −1 | | 1 | μA | 3 |
| Input High Current | V _{IH} | −1 | | 1 | μA | 3 |
| Antenna Port | | | | | | |
| RF Impedance | R _{IN} | | 50 | | Ω | |
| Receiver Section | | | | | | |
| Receiver Sensitivity | | | | | | |
| Tracking | | | −164 | | dBm | |
| Cold Start | | | −147 | | dBm | |
| Acquisition Time | | | | | | |
| Hot Start (Open Sky) | | | 1 | | s | |
| Hot Start (Indoor) | | | 30 | | s | |
| Cold Start | | | 33 | | s | |
| Cold Start, AGPS | | | 15 | | s | |
| Position Accuracy | | | | | | |
| Autonomous | | | 2.5 | | m | |
| SBAS | | | 2.5 | | m | |
| 1PPS Accuracy | | −11 | | 11 | ns | |
| Altitude | | | | 18,000 | m | |
| Velocity | | | | 515 | m/s | |
| Chipset | MediaTek MT3333 | | | | | |
| Frequency | GPS, GALILEO, QZSS: L1 1575.42MHz, C/A code GLONASS: L1 1598.0625MHz ~ 1605.375MHz, C/A code | | | | | |
| Channels | 99 | | | | | |
| Update Rate | 1Hz default, up to 10Hz | | | | | |
| Protocol Support | NMEA 0183 ver 4.10 | | | | | |
| 1. V _{CC} = 3.3V, without active antenna, ephemeris prediction is off | | | | | | |
| 2. V _{CC} = 0V | | | | | | |
| 3. No pull-up or pull-down on the lines | | | | | | |

Figure 4: Electrical Specifications

Pin Assignments

| | | | |
|---|---------|------|----|
| 1 | GND | NC | 18 |
| 2 | TX | NC | 17 |
| 3 | RX | NC | 16 |
| 4 | 1PPS | NC | 15 |
| 5 | NC | VOUT | 14 |
| 6 | VBACKUP | NC | 13 |
| 7 | NC | GND | 12 |
| 8 | VCC | RFIN | 11 |
| 9 | NC | GND | 10 |

Figure 5: TM Series GNSS Receiver Pinout (Top View)

Pin Descriptions

| Pin Descriptions | | | |
|-----------------------------|---------|-----|--------------------------------------------------------------------------------|
| Pin Number | Name | I/O | Description |
| 1, 10, 12 | GND | P | Ground |
| 2 | TX | O | Serial output (default NMEA) |
| 3 | RX | I | Serial input (default NMEA) |
| 4 | 1PPS | O | 1 Pulse Per Second (11nS accuracy) |
| 5, 7, 9, 13, 15, 16, 17, 18 | NC | – | No electrical connection |
| 6 | VBACKUP | P | Backup battery supply voltage. This line must be powered to enable the module. |
| 8 | VCC | P | Supply Voltage |
| 11 | RFIN | I | GNSS RF signal input |
| 14 | VOUT | O | Supply output for an active antenna |

Figure 6: TM Series GNSS Receiver Pin Descriptions

A Brief Overview of GNSS

Global Navigation Satellite System is a generic term that covers any system of satellites that are used to determine location on Earth and have global coverage. As of 2013 there are two fully operational GNSS systems; NAVSTAR GPS operated by the United States and GLONASS operated by Russia. The European Union is building its satellite constellation for their Galileo system and China has started to expand their Beidou system into a global system called Compass.

The United States has the original GNSS system consisting of a nominal constellation of 24 satellites orbiting the earth at about 12,000 nautical miles in height. The pattern and spacing of the satellites allow at least four to be visible above the horizon from any point on the Earth. Russia's GLONASS system fell into disrepair after the collapse of the Soviet Union, but was recovered and fully restored in 2011.

The systems were originally intended for military applications such as ordinance delivery and troop movement. In 1994 when the NAVSTAR constellation was completed, the GPS signals were made available for civilian applications, primarily aircraft navigation.

Each satellite transmits low power radio signals which contain three different bits of information; a pseudorandom code identifying the satellite, ephemeris data which contains the current date and time as well as the satellite's precise orbit information, and the almanac data which tells where each satellite should be at any time throughout the day and its status.

A receiver times the signals sent by multiple satellites and calculates the distance to each satellite. If the position of each satellite is known, the receiver can use triangulation to determine its position anywhere on the earth. The receiver uses four satellites to solve for four unknowns; latitude, longitude, altitude, and time. If any of these factors is already known to the system, an accurate position (fix) can be obtained with fewer satellites in view. Tracking more satellites improves calculation accuracy.

A faster Time To First Fix (TTFF) is possible if satellite information is stored in the receiver. If the receiver knows some of this information, then it can accurately predict satellite positions before acquiring an updated position fix. For example, aircraft or marine navigation equipment may have other means of determining altitude, so the GPS receiver would only have to lock on to three satellites and calculate three equations to provide the first position fix after power-up.

Time To First Fix (TTFF)

TTFF is often broken down into three parts:

Cold: A cold start is when the receiver has no accurate knowledge of its position or time. This happens when the receiver's internal Real Time Clock (RTC) has not been running or it has no valid ephemeris or almanac data. In a cold start, the receiver takes up to 30 seconds to acquire its position.

Warm: A typical warm start is when the receiver has valid almanac and time data and has not significantly moved since its last valid position calculation. This happens when the receiver has been shut down for more than 2 hours, but still has its last position, time, and almanac saved in memory, and its RTC has been running. The receiver can predict the location of the current visible satellites and its location; however, it needs to wait for an ephemeris broadcast (every 30 seconds) before it can accurately calculate its position.

Hot: A hot start is when the receiver has valid ephemeris, time, and almanac data. In a hot start, the receiver takes 1 second to acquire its position. The time to calculate a fix in this state is sometimes referred to as Time to Subsequent Fix or TTTF.

Module Description

The TM Series GNSS Receiver module is based on the MediaTek MT3333 chipset, which consumes less power than competitive products while providing exceptional performance even in dense foliage and urban canyons. No external RF components are needed other than an antenna. The simple serial interface and industry standard NMEA protocol make integration of the TM Series into an end product extremely straightforward.

The module's high-performance RF architecture allows it to receive GNSS signals that are as low as -164dBm . The TM Series can track up to 33 satellites at the same time. Once locked onto the visible satellites, the receiver calculates the range to the satellites and determines its position and the precise time. It then outputs the data through a standard serial port using several standard NMEA protocol formats.

The GNSS core handles all of the necessary initialization, tracking, and calculations autonomously, so no programming is required. The RF section is optimized for low level signals, and requires no production tuning.

Backup Battery

The module is designed to work with a backup battery that keeps the SRAM memory and the RTC powered when the RF section and the main GPS core are powered down. This enables the module to have a faster Time To First Fix (TTFF) when it is powered back on. The memory and clock pull about $7\mu\text{A}$. This means that a small lithium battery is sufficient to power these sections. This significantly reduces the power consumption and extends the main battery life while allowing for fast position fixes when the module is powered back on.

The backup battery must be installed for the module to be enabled.

Power Supply Requirements

The module requires a clean, well-regulated power source. While it is preferable to power the unit from a battery, it can operate from a power supply as long as noise is less than 20mV . Power supply noise can significantly affect the receiver's sensitivity, therefore providing clean power to the module should be a high priority during design. Bypass capacitors should be placed as close as possible to the module. The values should be adjusted depending on the amount and type of noise present on the supply line.

The 1PPS Output

The 1PPS line outputs 1 pulse per second on the rising edge of the GNSS second when the receiver has an over-solved navigation solution from five or more satellites. The pulse has a duration of 100ms with the rising edge on the GNSS second. This line is low until the receiver acquires a 3D fix. The GNSS second is based on the atomic clocks in the satellites, which are monitored and set to Universal Time master clocks. This output and the time calculated from the satellite transmissions can be used as a clock feature in an end product with $\pm 1\text{ns}$ accuracy.

Hybrid Ephemeris Prediction (AGPS)

AGPS is where the receiver uses the ephemeris data broadcast by the satellites to calculate models of each visible satellite's future location. This allows the receiver to store up to 3 days' worth of ephemeris data and results in faster TTFF. Having this data reduces the cold start time to less than 15 seconds. Contact Linx for details on this.

Antenna Considerations

The TM Series module is designed to utilize a wide variety of external antennas. The module has a regulated power output which simplifies the use of GNSS antenna styles which require external power. This allows the designer great flexibility, but care must be taken in antenna selection to ensure optimum performance. For example, a handheld device may be used in many varying orientations so an antenna element with a wide and uniform pattern may yield better overall performance than an antenna element with high gain and a correspondingly narrower beam. Conversely, an antenna mounted in a fixed and predictable manner may benefit from pattern and gain characteristics suited to that application. Evaluating multiple antenna solutions in real-world situations is a good way to rapidly assess which will best meet the needs of your application.

For GNSS, the antenna should have good right hand circular polarization characteristics (RHCP) to match the polarization of the GNSS signals. Ceramic patches are the most commonly used style of antenna, but there are many different shapes, sizes and styles of antennas available. Regardless of the construction, they will generally be either passive or active types. Passive antennas are simply an antenna tuned to the correct frequency. Active antennas add a Low Noise Amplifier (LNA) after the antenna and before the module to amplify the weak GPS satellite signals.

For active antennas, a 300-ohm ferrite bead can be used to connect the VOUT line to the RFIN line. This bead prevents the RF from getting into the power supply, but allows the DC voltage onto the RF trace to feed into the antenna. A series capacitor inside the module prevents this DC voltage from affecting the bias on the module's internal LNA.

Maintaining a 50-ohm path between the module and antenna is critical. Errors in layout can significantly impact the module's performance. Please review the layout guidelines section carefully to become more familiar with these considerations.

Power Control

The TM Series GPS Receiver module offers several ways to control the module's power. A serial command puts the module into a low-power standby mode that consumes only 365µA of current. An external processor can be used to power the module on and off to conserve battery power.

In addition, the module includes a duty cycle mode where the module will power on for a configurable amount of time to obtain a position fix then power off for a configurable amount of time. In this way the module can handle all of the timing without any intervention from the external processor.

There are four times that are configured with duty cycle mode. The on time and standby times are the amount of times that the module is on and in standby in normal operation. There are also cold start on and standby times. These are used to keep the module on longer in the event of a cold start so that it can gather the required satellite data for a position fix. After this, the module uses the normal operation times.

In the event that the module's stored ephemeris data becomes invalid the module supports and extended receive time to gather the required data from the satellites. Figure 7 shows the power control times.

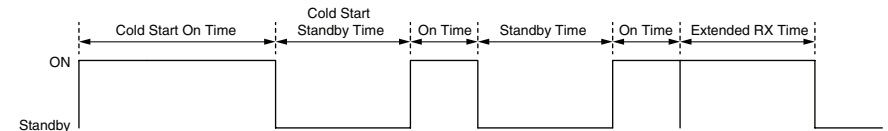


Figure 7: TM Series GNSS Receiver Power Control

The module supports MediaTek's proprietary AlwaysLocate™ mode. In this mode, the module automatically adapts the on and standby times to the current environmental conditions to balance position accuracy and power consumption. In this mode, any byte sent to the module triggers it to output the current position data.

Standby mode is configured by command 161. Extended receive time is configured by command 223. Command 225 configures which duty cycle mode is used.

Slow Start Time

The most critical factors in start time are current ephemeris data, signal strength and sky view. The ephemeris data describes the path of each satellite as they orbit the earth. This is used to calculate the position of a satellite at a particular time. This data is only usable for a short period of time, so if it has been more than a few hours since the last fix or if the location has significantly changed (a few hundred miles), then the receiver may need to wait for a new ephemeris transmission before a position can be calculated. The GNSS satellites transmit the ephemeris data every 30 seconds. Transmissions with a low signal strength may not be received correctly or be corrupted by ambient noise. The view of the sky is important because the more satellites the receiver can see, the faster the fix and the more accurate the position will be when the fix is obtained.

If the receiver is in a very poor location, such as inside a building, urban canyon, or dense foliage, then the time to first fix can be slowed. In very poor locations with poor signal strength and a limited view of the sky with outdated ephemeris data, this could be on the order of several minutes. In the worst cases, the receiver may need to receive almanac data, which describes the health and course data for every satellite in the constellation. This data is transmitted every 15 minutes. If a lock is taking a long time, try to find a location with a better view of the sky and fewer obstructions. Once locked, it is easier for the receiver to maintain the position fix.

Interfacing with NMEA Messages

Linux modules default to the NMEA protocol. Output messages are sent from the receiver on the TX line and input messages are sent to the receiver on the RX line. By default, output messages are sent once every second. Details of each message are described in the following sections.

The NMEA message format is as follows: <Message-ID + Data Payload + Checksum + End Sequence>. The serial data structure defaults to 9,600bps, 8 data bits, 1 stop bit, and no parity bits. Each message starts with a \$ character and ends with a <CR> <LF>. All fields within each message are separated by a comma. The checksum follows the * character and is the last two characters, not including the <CR> <LF>. It consists of two hex digits representing the exclusive OR (XOR) of all characters between, but not including, the \$ and * characters. When reading NMEA output messages, if a field has no value assigned to it, the comma will still be placed following the previous comma. For example, {04,,,,,2.0,} shows four empty fields between values 04 and 2.0. When writing NMEA input messages, all fields are required, none are optional. An empty field will invalidate the message and it will be ignored.

Reading NMEA output messages:

- Initialize a serial interface to match the serial data structure of the GPS receiver.
- Read the NMEA data from the TX pin into a receive buffer.
- Separate it into six buffers, one for each message type. Use the characters (\$) and <CR> <LF> as end points for each message.
- For each message, calculate the checksum as mentioned above to compare with the received checksum.
- Parse the data from each message using commas as field separators.
- Update the application with the parsed field values.
- Clear the receive buffer and be ready for the next set of messages.

Writing NMEA input messages:

- Initialize a serial interface to match the serial data structure of the GPS receiver.
- Assemble the message to be sent with the calculated checksum.
- Transmit the message to the receiver on the RX line.

NMEA Output Messages

The following sections outline the data structures of the various NMEA messages that are supported by the module. By default, the NMEA commands are output at 9,600bps, 8 data bits, no parity and 1 stop bit.

Six messages are output at a 1Hz rate by default. These messages are shown in Figure 8.

| NMEA Output Messages | |
|----------------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Name | Description |
| GGA | Contains the essential fix data which provide location and accuracy |
| GLL | Contains just position and time |
| GSA | Contains data on the Dilution of Precision (DOP) and which satellites are used |
| GSV | Contains the satellite location relative to the receiver and its signal to noise ratio. Each message can describe 4 satellites so multiple messages may be output depending on the number of satellites being tracked. |
| RMC | Contains the minimum data of time, position, speed and course |
| VTG | Contains the course and speed over the ground |

Figure 8: NMEA Output Messages

Some of the message IDs can change based on which system is used for the position fix. Figure 9 shows the different message identifiers based on the system that is used.

| NMEA Output Message Identifiers | | | | | | |
|---------------------------------|-------|-------|-------|----------------|--------------------------------|-------|
| System | GGA | GLL | GSA | GSV | RMC | VTG |
| GPS | GPGGA | GPGLL | GPGSA | GPGSV | GPRMC | GPVTG |
| GPS & GLONASS | GPGGA | GNGLL | GNGSA | GPGSV GLGSV | GPRMC or GNRMC ¹ | GPVTG |

1. The RMC output is GPRMC before a 3D fix, then changes to GNRMC after a fix is locked.

Figure 9: NMEA Output Message Identifiers

Details of each message and examples are given in the following sections.

GGA – Global Positioning System Fix Data

Figure 10 contains the values for the following example:

\$GPGGA,053740.000,2503.6319,N,12136.0099,E,1,08,1.1,63.8,M,15.2,M,,0000*64

| Global Positioning System Fix Data Example | | | |
|--------------------------------------------|------------|--------|-----------------------------------|
| Name | Example | Units | Description |
| Message ID | \$GPGGA | | GGA protocol header |
| UTC Time | 053740.000 | | hhmmss.sss |
| Latitude | 2503.6319 | | ddmm.mmmm |
| N/S Indicator | N | | N=north or S=south |
| Longitude | 12136.0099 | | dddmm.mmmm |
| E/W Indicator | E | | E=east or W=west |
| Position Fix Indicator | 1 | | See Figure 11 |
| Satellites Used | 08 | | Range 0 to 33 |
| HDOP | 1.1 | | Horizontal Dilution of Precision |
| MSL Altitude | 63.8 | meters | |
| Units | M | meters | |
| Geoid Separation | 15.2 | meters | |
| Units | M | meters | |
| Age of Diff. Corr. | | second | Null fields when DGPS is not used |
| Diff. Ref. Station | 0000 | | |
| Checksum | *64 | | |
| <CR> <LF> | | | End of message termination |

Figure 10: Global Positioning System Fix Data Example

| Position Indicator Values | |
|---------------------------|-------------------------------------------------------------|
| Value | Description |
| 0 | Fix not available or invalid |
| 1 | GPS SPS Mode, fix valid |
| 2 | Differential GPS, SPS Mode, fix valid |
| 3–5 | Not supported |
| 6 | Dead Reckoning Mode, fix valid (requires external hardware) |

Figure 11: Position Indicator Values

GLL – Geographic Position – Latitude / Longitude

Figure 12 contains the values for the following example:

\$GPGLL,2503.6319,N,12136.0099,E,053740.000,A,A*52

| Geographic Position – Latitude / Longitude Example | | | |
|----------------------------------------------------|------------|-------|------------------------------------------------------------------------|
| Name | Example | Units | Description |
| Message ID | \$GPGLL | | GLL protocol header (GNGLL or GPGLL) |
| Latitude | 2503.6319 | | ddmm.mmmm |
| N/S Indicator | N | | N=north or S=south |
| Longitude | 12136.0099 | | dddmm.mmmm |
| E/W Indicator | E | | E=east or W=west |
| UTC Time | 053740.000 | | hhmmss.sss |
| Status | A | | A=data valid or V=data not valid |
| Mode | A | | A=autonomous, D=DGPS, N=Data not valid, R=Coarse Position, S=Simulator |
| Checksum | *52 | | |
| <CR> <LF> | | | End of message termination |

Figure 12: Geographic Position – Latitude / Longitude Example

GSA – GNSS DOP and Active Satellites

Figure 13 contains the values for the following example:

\$GPGSA,A,3,24,07,17,11,28,08,20,04,,,,,2.0,1.1,1.7*35

| GNSS DOP and Active Satellites Example | | | |
|----------------------------------------|---------|-------|----------------------------------------------------------|
| Name | Example | Units | Description |
| Message ID | \$GPGSA | | GSA protocol header (GPGSA for GPS or GNGSA for GLONASS) |
| Mode 1 | A | | See Figure 14 |
| Mode 2 | 3 | | 1=No fix, 2=2D, 3=3D |
| ID of satellite used | 24 | | Sv on Channel 1 |
| ID of satellite used | 07 | | Sv on Channel 2 |
| ... | | | ... |
| ID of satellite used | | | Sv on Channel N |
| PDOP | 2.0 | | Position Dilution of Precision |
| HDOP | 1.1 | | Horizontal Dilution of Precision |
| VDOP | 1.7 | | Vertical Dilution of Precision |
| Checksum | *35 | | |
| <CR> <LF> | | | End of message termination |

Figure 13: GNSS DOP and Active Satellites Example

Mode 1 Values

| Value | Description |
|-------|---------------------------------------------------|
| M | Manual – forced to operate in 2D or 3D mode |
| A | Automatic – allowed to automatically switch 2D/3D |

Figure 14: Mode 1 Values

GSV – GNSS Satellites in View

Figure 15 contains the values for the following example:

\$GPGSV,3,1,12,28,81,285,42,24,67,302,46,31,54,354,,20,51,077,46*73

\$GPGSV,3,2,12,17,41,328,45,07,32,315,45,04,31,250,40,11,25,046,41*75

\$GPGSV,3,3,12,08,22,214,38,27,08,190,16,19,05,092,33,23,04,127,*7B

\$GLGSV,2,1,07,76,71,201,44,65,57,041,40,75,48,028,39,72,27,108,39*68

\$GLGSV,2,2,07,66,25,333,43,77,17,207,37,81,02,280,29*5C

GNSS Satellites in View Example

| Name | Example | Units | Description |
|---------------------------------------|---------|---------|-----------------------------------------------------------|
| Message ID | \$GPGSV | | GSV protocol header (GPGSV for GPS and GLGSV for GLONASS) |
| Total number of messages ¹ | 3 | | Range 1 to 6 (GPS) and 1 to 3 (GLONASS) |
| Message number ¹ | 1 | | Range 1 to 6 (GPS) and 1 to 3 (GLONASS) |
| Satellites in view | 12 | | |
| Satellite ID | 28 | | Channel 1 (Range 01 to 196) |
| Elevation | 81 | degrees | Channel 1 (Range 00 to 90) |
| Azimuth | 285 | degrees | Channel 1 (Range 000 to 359) |
| SNR (C/No) | 42 | dB-Hz | Channel 1 (Range 00 to 99, null when not tracking) |
| Satellite ID | 20 | | Channel 2 (Range 01 to 196) |
| Elevation | 51 | degrees | Channel 2 (Range 00 to 90) |
| Azimuth | 077 | degrees | Channel 2 (Range 000 to 359) |
| SNR (C/No) | 46 | dB-Hz | Channel 2 (Range 00 to 99, null when not tracking). |
| Checksum | *73 | | |
| <CR> <LF> | | | End of message termination |

1. Depending on the number of satellites tracked, multiple messages of GSV data may be required.

Figure 15: GNSS Satellites in View Example

RMC – Recommended Minimum Specific GNSS Data

Figure 16 contains the values for the following example:

\$GPRMC,053740.000,A,2503.6319,N,12136.0099,E,2.69,79.65,100106,,,A*53

| Recommended Minimum Specific GNSS Data Example | | | |
|------------------------------------------------|------------|---------|------------------------------------------------------------------------------|
| Name | Example | Units | Description |
| Message ID | \$GPRMC | | RMC protocol header (GNRMC or GPRMC) |
| UTC Time | 053740.000 | | hhmmss.sss |
| Status | A | | A=data valid or V=data not valid |
| Latitude | 2503.6319 | | ddmm.mmmm |
| N/S Indicator | N | | N=north or S=south |
| Longitude | 12136.0099 | | dddmm.mmmm |
| E/W Indicator | E | | E=east or W=west |
| Speed over ground | 2.69 | knots | TRUE |
| Course over ground | 79.65 | degrees | |
| Date | 100106 | | ddmmyy |
| Magnetic Variation | | degrees | Not available, null field |
| Variation Sense | | | E=east or W=west (not shown) |
| Mode | A | | A=autonomous, D=DGPS, E=DR, N=Data not valid, R=Coarse Position, S=Simulator |
| Checksum | *53 | | |
| <CR> <LF> | | | End of message termination |

Figure 16: Recommended Minimum Specific GNSS Data Example

VTG – Course Over Ground and Ground Speed

Figure 17 contains the values for the following example:

\$GPVTG,79.65,T,M,2.69,N,5.0,K,A*38

| Course Over Ground and Ground Speed Example | | | |
|---------------------------------------------|---------|---------|------------------------------------------------------------------------|
| Name | Example | Units | Description |
| Message ID | \$GPVTG | | VTG protocol header |
| Course over ground | 79.65 | degrees | Measured heading |
| Reference | T | | TRUE |
| Course over ground | | degrees | Measured heading (N/A, null field) |
| Reference | M | | Magnetic |
| Speed over ground | 2.69 | knots | Measured speed |
| Units | N | | Knots |
| Speed over ground | 5.0 | km/hr | Measured speed |
| Units | K | | Kilometer per hour |
| Mode | A | | A=autonomous, D=DGPS, N=Data not valid, R=Coarse Position, S=Simulator |
| Checksum | *38 | | |
| <CR> <LF> | | | End of message termination |

Figure 17: Course Over Ground and Ground Speed Example

Start-up Response

The module outputs a message when it starts up to indicate its state. The normal start-up message is shown below and the message formatting is shown in Figure 18.

\$PMTK010,001*2E<CR><LF>

| Start-up Response Example | | |
|---------------------------|-----------|---------------------------------------------------------------------------------------------------------------------------------------------------|
| Name | Example | Description |
| Message ID | \$PMTK010 | Message header |
| Message | MSG | System Message 0 = Unknown 1 = Start-up 2 = Notification for the host supporting EPO 3 = Transition to Normal operation is successful |
| Checksum | CKSUM | |
| End Sequence | <CR> <LF> | End of message termination |

Figure 18: Start-up Response Example

Input Messages

The following outlines the serial commands input into the module for configuration. There are 3 types of input messages: commands, writes and reads. The module outputs a response for each input message.

The commands are used to change the operating state of the module. The writes are used to change the module's configuration and the reads are used to read out the current configuration. Messages are formatted as shown in Figure 19. All fields in each message are separated by a comma.

| Serial Data Structure | | |
|-----------------------|-----------|-------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Name | Example | Description |
| Start Sequence | \$PMTK | |
| Message ID | <MID> | Message Identifier consisting of three numeric characters. |
| Payload | DATA | Message specific data. |
| Checksum | CKSUM | CKSUM is a two-hex character checksum as defined in the NMEA specification, NMEA-0183 Standard for Interfacing Marine Electronic Devices. Checksums are required on all input messages. |
| End Sequence | <CR> <LF> | Each message must be terminated using Carriage Return (CR) Line Feed (LF) (\r\n, 0x0D0A) to cause the receiver to process the input message. They are not printable ASCII characters, so are omitted from the examples. |

Figure 19: Serial Data Structure

Figure 20 shows the input commands.

| Input Commands | |
|----------------|-------------------------------|
| Name | Description |
| 101 | Hot Re-start |
| 102 | Warm Re-start |
| 103 | Cold Re-start |
| 104 | Restore Default Configuration |
| 161 | Standby Mode |
| 220 | Position Fix Interval |
| 223 | Ephemeris Data Receive Time |
| 225 | Receiver Duty Cycle |
| 251 | Baud Rate |

Figure 20: Input Commands

The write and read messages are shown in Figure 21. A write message triggers an acknowledgement from the module. A read message triggers a response message containing the requested information.

| Input Write and Read Messages | | | |
|-------------------------------|----------|---------|-------------|
| Description | Write ID | Read ID | Response ID |
| Position Fix Interval | 300 | 400 | 500 |
| DGPS Source | 301 | 401 | 501 |
| SBAS Enable | 313 | 413 | 513 |
| NMEA Output Messages | 314 | 414 | 514 |
| Set Datum | 330 | 430 | 530 |
| GNSS Search System | 353 | — | — |
| Static Navigation Threshold | 386 | 447 | 527 |
| Enable Ephemeris Prediction | 869 | 869 | 869 |

Figure 21: Input Write and Read Messages

The module responds to commands with response messages. The acknowledge message is formatted as shown in Figure 22.

| Acknowledge Message | | |
|---------------------|-----------|-------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Name | Example | Description |
| Start Sequence | \$PMTK | |
| Message ID | 001 | Acknowledge Identifier |
| Command | CMD | The command that triggered the acknowledge |
| Flag | Flg | Flag indicating the outcome of the command 0 = Invalid Command 1 = Unsupported Command 2 = Valid command, but action failed 3 = Valid command and action succeeded |
| Checksum | CKSUM | CKSUM is a two-hex character checksum as defined in the NMEA specification, NMEA-0183 Standard for Interfacing Marine Electronic Devices. Checksums are required on all input messages. |
| End Sequence | <CR> <LF> | Each message must be terminated using Carriage Return (CR) Line Feed (LF) (\r\n, 0x0D0A) to cause the receiver to process the input message. They are not printable ASCII characters, so are omitted from the examples. |

Figure 22: Acknowledge Message

101 – Hot Re-start

This command instructs the module to conduct a hot re-start using all of the data stored in memory. Periodic mode and static navigation settings are returned to default when this command is executed.

```
$PMTK101*32<CR><LF>
```

102 – Warm Re-start

This command instructs the module to conduct a warm re-start that does not use the saved ephemeris data. Periodic mode and static navigation settings are returned to default when this command is executed.

```
$PMTK102*31<CR><LF>
```

103 – Cold Re-start

This command instructs the module to conduct a cold re-start that does not use any of the data from memory. Periodic mode and static navigation settings are returned to default when this command is executed.

```
$PMTK103*30<CR><LF>
```

104 – Restore Default Configuration

This command instructs the module to conduct a cold re-start and return all configurations to the factory default settings.

```
$PMTK104*37<CR><LF>
```

161 – Standby Mode

This command instructs the module to enter a low power standby mode. Any activity on the RX line wakes the module.

```
$PMTK161,0*28<CR><LF>
```

The module outputs the startup message when it wakes up.

```
$PMTK010,001*2E<CR><LF>
```

220 – Position Fix Interval

This command sets the position fix interval. This is the time between when the module calculates its position. This is the same as write message 300.

Position Fix Interval Command and Response

Command

| Start | Msg ID | Interval | Checksum | End |
|--------|--------|----------|----------|----------|
| \$PMTK | 220 | ,lval | *Cksum | <CR><LF> |

Response

| Start | Msg ID | CMD | Flag | Checksum | End |
|--------|--------|------|------|----------|----------|
| \$PMTK | 001 | ,220 | ,Flg | *Cksum | <CR><LF> |

Figure 23: Position Fix Interval Command and Response

lval = the interval time in milliseconds.

The interval must be larger than 100ms. Faster rates require that the baud rate be increased, the number of messages that are output be decreased or both. The module automatically calculates the required data bandwidth and returns an action failed response (Flg = 2) if the interval is faster than the module can output all of the required messages at the current baud rate. The following example sets the interval to 1 second.

```
$PMTK220,1000*1F<CR><LF>
```

223 – Extended Receive Time

This command extends the amount of time that the receiver is on when in duty cycle mode. This allows the module to refresh its stored ephemeris data by staying awake until it received the data from the satellites.

| Extended Receive Time Command and Response | | | | | | | |
|--------------------------------------------|--------|------|---------|-------------|------------|----------|----------|
| Command | | | | | | | |
| Start | Msg ID | SV | On Time | Extend Time | Extend Gap | Checksum | End |
| \$PMTK | 223 | ,SV | ,SNR | ,EXT | ,EXG | *Cksum | <CR><LF> |
| Response | | | | | | | |
| Start | Msg ID | CMD | Flag | Checksum | End | | |
| \$PMTK | 001 | ,223 | ,Flg | *Cksum | <CR><LF> | | |

Figure 24: Extended Receive Time Command and Response

| Extended Receive Time Fields | |
|------------------------------|--------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Field | Description |
| SV | The minimum number of satellites required to have valid ephemeris data. The extend time triggers when the number of satellites with valid ephemeris data falls below this number. The value is 1 to 4. |
| SNR | The minimum SNR of the satellites used for a position fix. The module will not wait for ephemeris data from any satellites whose SNR is below this value. |
| EXT | The extended time in ms to stay on to receive ephemeris data. This value can range from 40000 to 180000. |
| EXG | The minimum time in ms between a subsequent extended receive period. This value can range from 0 to 3600000. |

Figure 25: Extended Receive Time Fields

The following example configures an extended on time to trigger if less than 1 satellite has valid ephemeris data. The satellite must have a signal to noise ratio higher than 30dB-Hz in order to be used. The module will stay on for 180,000ms and will have a gap time of 60,000ms.

```
$PMTK223,1,30,180000,60000*16<CR><LF>
```

225 – Receiver Duty Cycle

This command places the module into a duty cycle where it stays on for a period of time and calculates its position then goes to sleep for a period of time. This conserves battery power without the need for an external microcontroller to manage the timing.

| Receiver Duty Cycle Command and Response | | | | | | | | |
|------------------------------------------|--------|------|---------|--------------|----------|------------|----------|----------|
| Command | | | | | | | | |
| Start | Msg ID | Mode | On Time | Standby Time | Cold On | Cold Sleep | Checksum | End |
| \$PMTK | 225 | ,Mde | ,TO | ,TS | ,CO | ,CS | *Cksum | <CR><LF> |
| Response | | | | | | | | |
| Start | Msg ID | CMD | Flag | Checksum | End | | | |
| \$PMTK | 001 | ,225 | ,Flg | *Cksum | <CR><LF> | | | |

Figure 26: Receiver Duty Cycle Command and Response

| Receiver Duty Cycle Fields | |
|----------------------------------------------------------------------------------|----------------------------------------------------------------------------------------------------------------------------------------------|
| Field | Description |
| Mde | Operation Mode 0 = Normal Mode 2 = Duty Cycle Mode 8 = AlwaysLocate™ |
| TO | Receiver on time (ms) |
| TS | Receiver standby time (ms) |
| CO | Receiver on time in the event of a cold start (ms). Allows more time for the module to receive ephemeris data in the event of a cold start. |
| CS | Receiver off time in the event of a cold start (ms). Allows more time for the module to receive ephemeris data in the event of a cold start. |
| CR and CS can be null values. In this case the module uses the TO and TS values. | |

Figure 27: Receiver Duty Cycle Fields

This example sets the mode to duty cycle with an on time of 3s, and off time of 12s, a cold start on time of 18s and a cold start off time of 72s.

```
$PMTK225,2,3000,12000,18000,72000*15<CR><LF>
```

The following example sets the mode to normal operation.

```
$PMTK225,0*2B<CR><LF>
```

The following example sets the module into AlwaysLocate™ mode.

```
$PMTK225,8*23<CR><LF>
```

251 – Baud Rate

This command sets the serial port baud rate.

Serial Port Baud Rate Command and Response

Command

| | | | | |
|--------|--------|-------|----------|----------|
| Start | Msg ID | Rate | Checksum | End |
| \$PMTK | 251 | ,Rate | *Cksum | <CR><LF> |

Response

| | | | | | |
|--------|--------|------|------|----------|----------|
| Start | Msg ID | CMD | Flag | Checksum | End |
| \$PMTK | 001 | ,251 | ,Flg | *Cksum | <CR><LF> |

Figure 28: Serial Port Baud Rate Command and Response

Rate = serial port baud rate

0 = default setting

4800

9600

14400

19200

38400

57600

115200

The following example sets the baud rate to 57,600bps.

```
$PMTK251,57600*2C<CR><LF>
```

Position Fix Interval

This configures the position fix interval. This is the time between when the module calculates its position. This is the same as write message 220.

Position Fix Interval Command and Response

Write Message

| | | | | | |
|--------|--------|----------|----------|----------|----------|
| Start | Msg ID | Interval | Data | Checksum | End |
| \$PMTK | 300 | ,lval | ,0,0,0,0 | *Cksum | <CR><LF> |

Acknowledge Response Message

| | | | | | |
|--------|--------|------|------|----------|----------|
| Start | Msg ID | CMD | Flag | Checksum | End |
| \$PMTK | 001 | ,300 | ,Flg | *Cksum | <CR><LF> |

Read Message

| | | | |
|--------|--------|----------|----------|
| Start | Msg ID | Checksum | End |
| \$PMTK | 400 | *36 | <CR><LF> |

Response Message

| | | | | | |
|--------|--------|----------|----------|----------|----------|
| Start | Msg ID | Interval | Data | Checksum | End |
| \$PMTK | 500 | ,lval | ,0,0,0,0 | *Cksum | <CR><LF> |

Figure 29: Position Fix Interval Command and Response

lval = the interval time in milliseconds.

The interval must be larger than 100ms. Faster rates require that the baud rate be increased, the number of messages that are output be decreased or both. The module automatically calculates the required data bandwidth and returns an action failed response (Flg = 2) if the interval is faster than the module can output all of the required messages at the current baud rate.

The following example sets the interval to 1 second.

```
$PMTK300,1000,0,0,0,0*1C<CR><LF>
```

The following example reads the current position fix interval and the module responds with an interval time of 1 second (1,000ms)

```
$PMTK400*36<CR><LF>
```

```
$PMTK500,1000,0,0,0,0*1A<CR><LF>
```


DGPS Source

This enables or disables DGPS mode and configures its source.

DGPS Souce Command and Response

Write Message

| | | | | |
|--------|--------|-------|----------|----------|
| Start | Msg ID | Mode | Checksum | End |
| \$PMTK | 301 | ,Mode | *Cksum | <CR><LF> |

Acknowledge Response Message

| | | | | | |
|--------|--------|------|------|----------|----------|
| Start | Msg ID | CMD | Flag | Checksum | End |
| \$PMTK | 001 | ,301 | ,Flg | *Cksum | <CR><LF> |

Read Message

| | | | |
|--------|--------|----------|----------|
| Start | Msg ID | Checksum | End |
| \$PMTK | 401 | *37 | <CR><LF> |

Response Message

| | | | | |
|--------|--------|-------|----------|----------|
| Start | Msg ID | Mode | Checksum | End |
| \$PMTK | 501 | ,Mode | *Cksum | <CR><LF> |

Figure 30: DGPS Source Command and Response

Mode = DGPS source mode

- 0 = No DGPS source
- 1 = RTCM
- 2 = WAAS

Differential Global Positioning System (DGPS) enhances GPS by using fixed, ground-based reference stations that broadcast the difference between the positions indicated by the satellite systems and the known fixed positions. The Radio Technical Commission for Maritime Services (RTCM) is an international standards organization that has a standard for DGPS. Wide Area Augmentation System (WAAS) is maintained by the FAA to improve aircraft navigation. This setting automatically switches among WAAS, EGNOS, MSAS and GAGAN when detected in covered regions

The following example sets the DGPS source to RTCM.

```
$PMTK301,1*2D<CR><LF>
```

The following example reads the current DGPS source and the module responds with the DGPS source as RTCM.

```
$PMTK401*37<CR><LF>
$PMTK501,1*2B<CR><LF>
```

SBAS Enable

This enables and disables SBAS.

SBAS Enable Command and Response

Write Message

| | | | | |
|--------|--------|-------|----------|----------|
| Start | Msg ID | Mode | Checksum | End |
| \$PMTK | 313 | ,Mode | *Cksum | <CR><LF> |

Acknowledge Response Message

| | | | | | |
|--------|--------|------|------|----------|----------|
| Start | Msg ID | CMD | Flag | Checksum | End |
| \$PMTK | 001 | ,313 | ,Flg | *Cksum | <CR><LF> |

Read Message

| | | | |
|--------|--------|----------|----------|
| Start | Msg ID | Checksum | End |
| \$PMTK | 413 | *34 | <CR><LF> |

Response Message

| | | | | |
|--------|--------|-------|----------|----------|
| Start | Msg ID | Mode | Checksum | End |
| \$PMTK | 513 | ,Mode | *Cksum | <CR><LF> |

Figure 31: SBAS Enable Command and Response

Mode = SBAS Mode

- 0 = disabled
- 1 = enabled

A satellite-based augmentation system (SBAS) sends additional information in the satellite transmissions to improve accuracy and reliability. Ground stations at accurately surveyed locations measure the satellite signals or other environmental factors that may impact the signal received by users. Correction information is then sent to the satellites and broadcast to the users. Disabling this feature also disables automatic DGPS.

The following example enables SBAS.

```
$PMTK313,1*2E<CR><LF>
```

The following example reads the current SBAS configuration and the module responds with SBAS is enabled.

```
$PMTK413*34<CR><LF>
$PMTK513,1*28<CR><LF>
```

This configures how often each NMEA output message is output.

NMEA Output Messages Command and Response

Write Message

| | | | | | | | | | | |
|--------|--------|------|------|------|------|------|------|----------------------------------|----------|-----|
| Start | Msg ID | GLL | RMC | VTG | GGA | GSA | GSV | DATA | CK | End |
| \$PMTK | 314 | ,GLL | ,RMC | ,VTG | ,GGA | ,GSA | ,GSV | ,0,0,0,0,0,0,0,0,0,0,0,0,0,0,*CK | <CR><LF> | |

Acknowledge Response Message

| | | | | | |
|--------|--------|------|------|-----|----------|
| Start | Msg ID | CMD | Flag | CK | End |
| \$PMTK | 001 | ,314 | ,Flg | *CK | <CR><LF> |

Read Message

| | | | |
|--------|--------|-----|----------|
| Start | Msg ID | CK | End |
| \$PMTK | 414 | *33 | <CR><LF> |

Response Message

| | | | | | | | | | | |
|--------|--------|------|------|------|------|------|------|--------------------------------|----------|-----|
| Start | Msg ID | GLL | RMC | VTG | GGA | GSA | GSV | DATA | CK | End |
| \$PMTK | 514 | ,GLL | ,RMC | ,VTG | ,GGA | ,GSA | ,GSV | ,0,0,0,0,0,0,0,0,0,0,0,0,0,*CK | <CR><LF> | |

Figure 32: NMEA Output Messages Command and Response

Each field has a value of 1 through 5 which indicates how many position fixes should be between each time the message is output. A 1 configures the message to be output every position fix. A value of 2 configures the message to be output every other position fix and a value of 5 configures it to be output every 5th position fix. This along with message 220 or 300 sets the time between message outputs.

A value of 0 disables the message.

The example below sets all of the messages to be output every fix.

```
$PMTK314,1,1,1,1,1,1,0,0,0,0,0,0,0,0,0,0,0,0*28<CR><LF>
```

The following example reads the current message configuration and the module responds that all supported messages are configured to be output on every position fix.

```
$PMTK414*33<CR><LF>
```

```
$PMTK514,1,1,1,1,1,1,0,0,0,0,0,0,0,0,0,0,0,0*2E<CR><LF>
```

Set Datum

This configures the current datum that is used.

Set Datum Command and Response

Write Message

| Start | Msg ID | Datum | Checksum | End |
|--------|--------|--------|----------|----------|
| \$PMTK | 330 | ,Datum | *Cksum | <CR><LF> |

Acknowledge Response Message

| Start | Msg ID | CMD | Flag | Checksum | End |
|--------|--------|------|------|----------|----------|
| \$PMTK | 001 | ,330 | ,Flg | *Cksum | <CR><LF> |

Read Message

| Start | Msg ID | Checksum | End |
|--------|--------|----------|----------|
| \$PMTK | 430 | *35 | <CR><LF> |

Response Message

| Start | Msg ID | Datum | Checksum | End |
|--------|--------|--------|----------|----------|
| \$PMTK | 530 | ,Datum | *Cksum | <CR><LF> |

Figure 33: Set Datum Command and Response

Datum = the datum number to be used.

Reference datums are data sets that describe the shape of the Earth based on a reference point. There are many regional datums based on a convenient local reference point. Different datums use different reference points, so a map used with the receiver output must be based on the same datum. WGS84 is the default world referencing datum.

The module supports 223 different datums. These are listed in Appendix A.

The following example sets the datum to WGS84.

\$PMTK330,0*2E<CR><LF>

The following example reads the current datum and the module replies with datum 0, which is WGS84.

\$PMTK430*35<CR><LF>

\$PMTK530,0*28<CR><LF>

GNSS Search System

This configures the GNSS systems used to calculate position fixes.

| GNSS Search System Command and Response | | | | | |
|-----------------------------------------|--------|------|---------|----------|----------|
| Write Message | | | | | |
| Start | Msg ID | GPS | GLONASS | Checksum | End |
| \$PMTK | 353 | ,GPS | ,GLNS | *Cksum | <CR><LF> |
| Acknowledge Response Message | | | | | |
| Start | Msg ID | CMD | Flag | Checksum | End |
| \$PMTK | 001 | ,353 | ,Flg | *Cksum | <CR><LF> |

Figure 34: GNSS Search System Command and Response

GPS = Search GPS satellites

0 = disabled, do not search GPS satellites

1 = enabled

GLNS = Search GLONASS satellites

0 = disabled, do not search GLONASS satellites

1 = enabled

The following example configures the module to only use GLONASS satellites.

```
$PMTK353,0,1*36<CR><LF>
```

The following example configures the module to only use GPS satellites.

```
$PMTK353,1,0*36<CR><LF>
```

The following example configures the module to use GPS and GLONASS satellites.

```
$PMTK353,1,1*36<CR><LF>
```

Static Navigation Threshold

This configures the speed threshold to trigger static navigation. If the measured speed is below the threshold then the module holds the current position and sets the speed to zero.

Static Navigation Threshold Command and Response

Write Message

| | | | | |
|--------|--------|--------|----------|----------|
| Start | Msg ID | Thold | Checksum | End |
| \$PMTK | 386 | ,Thold | *Cksum | <CR><LF> |

Acknowledge Response Message

| | | | | | |
|--------|--------|------|------|----------|----------|
| Start | Msg ID | CMD | Flag | Checksum | End |
| \$PMTK | 001 | ,386 | ,Flg | *Cksum | <CR><LF> |

Read Message

| | | | |
|--------|--------|----------|----------|
| Start | Msg ID | Checksum | End |
| \$PMTK | 447 | *35 | <CR><LF> |

Response Message

| | | | | |
|--------|--------|--------|----------|----------|
| Start | Msg ID | Thold | Checksum | End |
| \$PMTK | 527 | ,Thold | *Cksum | <CR><LF> |

Figure 35: Static Navigation Threshold Command and Response

Thold = speed threshold, from 0 to 2.0m/s. 0 = disabled.

The following example sets the threshold to 1.2m/s.

```
$PMTK386,1.2*3E<CR><LF>
```

The following example reads the static navigation threshold and the module responds with 1.2m/s

```
$PMTK447*35<CR><LF>
```

```
$PMTK527,1.20*03<CR><LF>
```

Enable Ephemeris Prediction

This enables or disables the module's built-in ephemeris prediction.

| Enable Ephemeris Prediction Command and Response | | | | | |
|--------------------------------------------------|--------|------|---------|----------|----------|
| Write Message | | | | | |
| Start | Msg ID | CMD | Enable | Checksum | End |
| \$PMTK | 869 | ,1 | ,Enable | *Cksum | <CR><LF> |
| Acknowledge Response Message | | | | | |
| Start | Msg ID | CMD | Flag | Checksum | End |
| \$PMTK | 001 | ,869 | ,Flg | *Cksum | <CR><LF> |
| Read Message | | | | | |
| Start | Msg ID | CMD | Enable | Checksum | End |
| \$PMTK | 869 | ,0 | ,Enable | *Cksum | <CR><LF> |
| Response Message | | | | | |
| Start | Msg ID | CMD | Enable | Checksum | End |
| \$PMTK | 869 | ,2 | ,Enable | *Cksum | <CR><LF> |

Figure 36: Enable Ephemeris Prediction Command and Response

This message is formatted slightly differently from the other messages. The same Message ID is used for the read, write and response and the first payload field (CMD) indicates which type of message it is. A 0 is a read, a 1 is a write and a 2 is a response to a read.

Enable = enable ephemeris prediction

0 = disabled

1 = enabled

The following example enables prediction.

```
$PMTK869,1,1*35<CR><LF>
```

The following example reads the configuration.

```
$PMTK869,0*29<CR><LF>
```

The module responds with the first example if prediction is disabled and the second if it is enabled.

```
$PMTK869,2,0*37<CR><LF>
```

```
$PMTK869,2,1*36<CR><LF>
```

Typical Applications

Figure 37 shows the TM Series GNSS receiver in a typical application using a passive antenna.

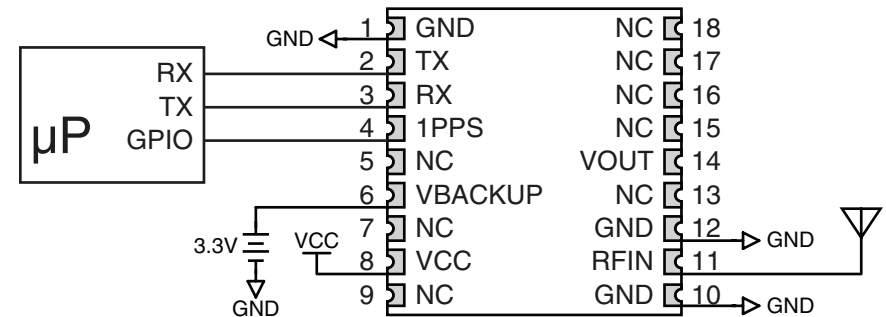


Figure 37: Circuit Using the TM Series Module with a Passive Antenna

A microcontroller UART is connected to the receiver's UART for passing data and commands. A 3.3V coin cell battery is connected to the VBACKUP line to provide power to the module's memory when main power is turned off.

Figure 38 shows the module using an active antenna.

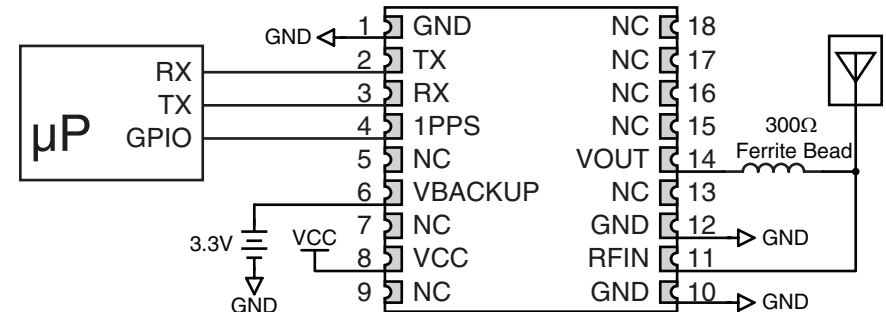


Figure 38: Circuit Using the TM Series Module with a an Active Antenna

A 300Ω ferrite bead is used to put power from VOUT onto the antenna line to power the active antenna.

Master Development System

The TM Series Master Development System provides all of the tools necessary to evaluate the TM Series GNSS receiver module. The system includes a fully assembled development board, an active antenna, development software and full documentation.

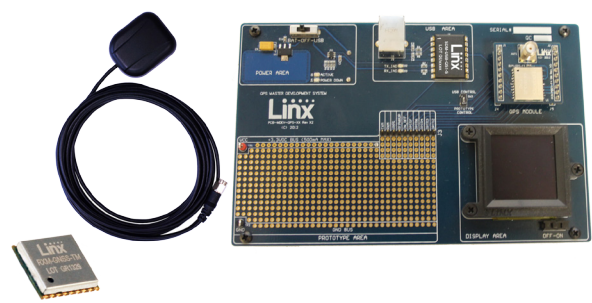


Figure 39: The TM Series Master Development System

The development board includes a power supply, a prototyping area for custom circuit development, and an OLED display that shows the GPS data without the need for a computer. A USB interface is also included for use with a PC running custom software or the included development software.



Figure 40: The Master Development System Software

The Master Development System software enables configuration of the receiver and displays the satellite data output by the receiver. The software can select from among all of the supported NMEA protocols for display of the data.

Full documentation for the board and software is included in the development system, making integration of the module straightforward.

Microstrip Details

A transmission line is a medium whereby RF energy is transferred from one place to another with minimal loss. This is a critical factor, especially in high-frequency products like Linx RF modules, because the trace leading to the module's antenna can effectively contribute to the length of the antenna, changing its resonant bandwidth. In order to minimize loss and detuning, some form of transmission line between the antenna and the module should be used unless the antenna can be placed very close (<1/8in) to the module. One common form of transmission line is a coax cable and another is the microstrip. This term refers to a PCB trace running over a ground plane that is designed to serve as a transmission line between the module and the antenna. The width is based on the desired characteristic impedance of the line, the thickness of the PCB and the dielectric constant of the board material. For standard 0.062in thick FR-4 board material, the trace width would be 111 mils. The correct trace width can be calculated for other widths and materials using the information in Figure 41 and examples are provided in Figure 42. Software for calculating microstrip lines is also available on the Linx website.

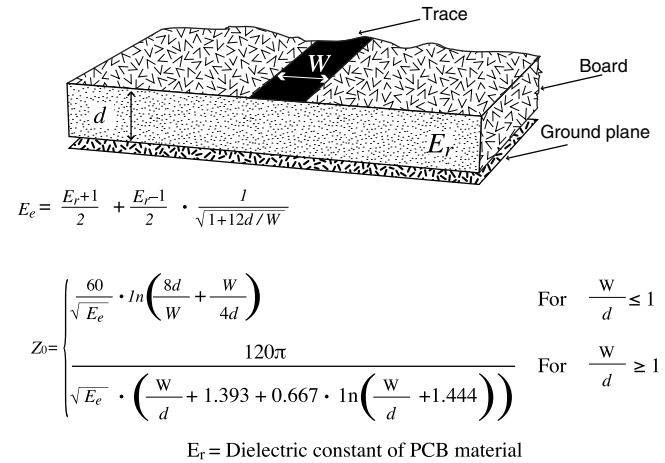


Figure 41: Microstrip Formulas

| Example Microstrip Calculations | | | |
|---------------------------------|--------------------------|-------------------------------|------------------------------|
| Dielectric Constant | Width/Height Ratio (W/d) | Effective Dielectric Constant | Characteristic Impedance (Ω) |
| 4.80 | 1.8 | 3.59 | 50.0 |
| 4.00 | 2.0 | 3.07 | 51.0 |
| 2.55 | 3.0 | 2.12 | 48.0 |

Figure 42: Example Microstrip Calculations

Board Layout Guidelines

The module's design makes integration straightforward; however, it is still critical to exercise care in PCB layout. Failure to observe good layout techniques can result in a significant degradation of the module's performance. A primary layout goal is to maintain a characteristic 50-ohm impedance throughout the path from the antenna to the module. Grounding, filtering, decoupling, routing and PCB stack-up are also important considerations for any RF design. The following section provides some basic design guidelines which may be helpful.

During prototyping, the module should be soldered to a properly laid-out circuit board. The use of prototyping or “perf” boards will result in poor performance and is strongly discouraged.

The module should, as much as reasonably possible, be isolated from other components on your PCB, especially high-frequency circuitry such as crystal oscillators, switching power supplies, and high-speed bus lines.

When possible, separate RF and digital circuits into different PCB regions. Make sure internal wiring is routed away from the module and antenna, and is secured to prevent displacement.

Do not route PCB traces directly under the module. There should not be any copper or traces under the module on the same layer as the module, just bare PCB. The underside of the module has traces and vias that could short or couple to traces on the product's circuit board.

The Pad Layout section shows a typical PCB footprint for the module. A ground plane (as large and uninterrupted as possible) should be placed on a lower layer of your PC board opposite the module. This plane is essential for creating a low impedance return for ground and consistent stripline performance.

Use care in routing the RF trace between the module and the antenna or connector. Keep the trace as short as possible. Do not pass under the module or any other component. Do not route the antenna trace on multiple PCB layers as vias will add inductance. Vias are acceptable for tying together ground layers and component grounds and should be used in multiples.

Each of the module's ground pins should have short traces tying immediately to the ground plane through a via.

Bypass caps should be low ESR ceramic types and located directly adjacent to the pin they are serving.

A 50-ohm coax should be used for connection to an external antenna. A 50-ohm transmission line, such as a microstrip, stripline or coplanar waveguide should be used for routing RF on the PCB. The Microstrip Details section provides additional information.

In some instances, a designer may wish to encapsulate or “pot” the product. There is a wide variety of potting compounds with varying dielectric properties. Since such compounds can considerably impact RF performance and the ability to rework or service the product, it is the responsibility of the designer to evaluate and qualify the impact and suitability of such materials.

Pad Layout

The pad layout diagram in Figure 43 is designed to facilitate both hand and automated assembly.

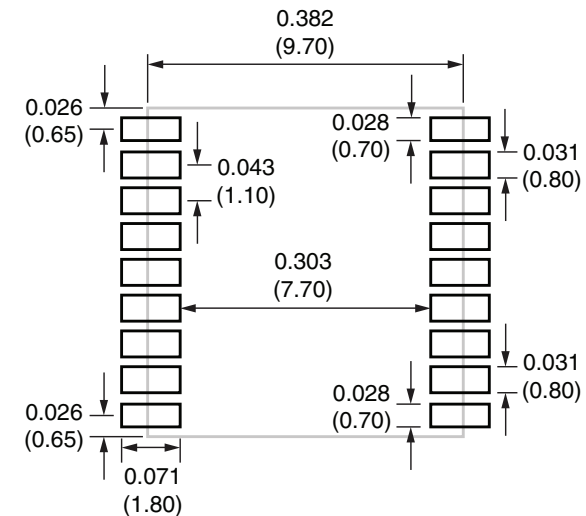


Figure 43: Recommended PCB Layout

Production Guidelines

The module is housed in a hybrid SMD package that supports hand and automated assembly techniques. Since the modules contain discrete components internally, the assembly procedures are critical to ensuring the reliable function of the modules. The following procedures should be reviewed with and practiced by all assembly personnel.

Hand Assembly

Pads located on the bottom of the module are the primary mounting surface (Figure 44). Since these pads are inaccessible during mounting, castellations that run up the side of the module have been provided to facilitate solder wicking to the module's underside. This allows for very

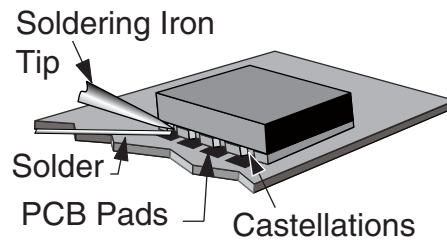


Figure 44: Soldering Technique

quick hand soldering for prototyping and small volume production. If the recommended pad guidelines have been followed, the pads will protrude slightly past the edge of the module. Use a fine soldering tip to heat the board pad and the castellation, then introduce solder to the pad at the module's edge. The solder will wick underneath the module, providing reliable attachment. Tack one module corner first and then work around the device, taking care not to exceed the times in Figure 45.

Warning: Pay attention to the absolute maximum solder times.

Absolute Maximum Solder Times

Hand Solder Temperature: +427°C for 10 seconds for lead-free alloys

Reflow Oven: +240°C max (see Figure 46)

Figure 45: Absolute Maximum Solder Times

Automated Assembly

For high-volume assembly, the modules are generally auto-placed. The modules have been designed to maintain compatibility with reflow processing techniques; however, due to their hybrid nature, certain aspects of the assembly process are far more critical than for other component types. Following are brief discussions of the three primary areas where caution must be observed.

Reflow Temperature Profile

The single most critical stage in the automated assembly process is the reflow stage. The reflow profile in Figure 46 should not be exceeded because excessive temperatures or transport times during reflow will irreparably damage the modules. Assembly personnel need to pay careful attention to the oven's profile to ensure that it meets the requirements necessary to successfully reflow all components while still remaining within the limits mandated by the modules. The figure below shows the recommended reflow oven profile for the modules.

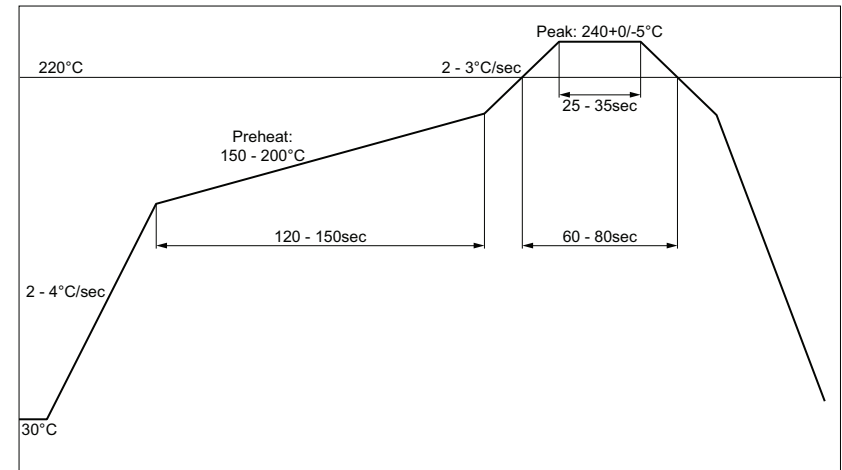


Figure 46: Maximum Reflow Temperature Profile

Shock During Reflow Transport

Since some internal module components may reflow along with the components placed on the board being assembled, it is imperative that the modules not be subjected to shock or vibration during the time solder is liquid. Should a shock be applied, some internal components could be lifted from their pads, causing the module to not function properly.

Washability

The modules are wash-resistant, but are not hermetically sealed. Linx recommends wash-free manufacturing; however, the modules can be subjected to a wash cycle provided that a drying time is allowed prior to applying electrical power to the modules. The drying time should be sufficient to allow any moisture that may have migrated into the module to evaporate, thus eliminating the potential for shorting damage during power-up or testing. If the wash contains contaminants, the performance may be adversely affected, even after drying.

Appendix A

The following datums are supported by the TM Series.

| TM Series GNSS Receiver Supported Datums | | |
|------------------------------------------|--------------------------|------------------------------------------------------------------------|
| Number | Datum | Region |
| 0 | WGS1984 | International |
| 1 | Tokyo | Japan |
| 2 | Tokyo | Mean for Japan, South Korea, Okinawa |
| 3 | User Setting | User Setting |
| 4 | Adindan | Burkina Faso |
| 5 | Adindan | Cameroon |
| 6 | Adindan | Ethiopia |
| 7 | Adindan | Mali |
| 8 | Adindan | Mean for Ethiopia, Sudan |
| 9 | Adindan | Senegal |
| 10 | Adindan | Sudan |
| 11 | Afgooye | Somalia |
| 12 | Ain El Abd1970 | Bahrain |
| 13 | Ain El Abd1970 | Saudi Arabia |
| 14 | American Samoa1962 | American Samoa Islands |
| 15 | Anna 1 Astro1965 | Cocos Island |
| 16 | Antigua Island Astro1943 | Antigua(Leeward Islands) |
| 17 | Arc1950 | Botswana |
| 18 | Arc1950 | Burundi |
| 19 | Arc1950 | Lesotho |
| 20 | Arc1950 | Malawi |
| 21 | Arc1950 | Mean for Botswana, Lesotho, Malawi, Swaziland, Zaire, Zambia, Zimbabwe |
| 22 | Arc1950 | Swaziland |
| 23 | Arc1950 | Zaire |
| 24 | Arc1950 | Zambia |
| 25 | Arc1950 | Zimbabwe |
| 26 | Arc1960 | Mean For Kenya Tanzania |
| 27 | Arc1960 | Kenya |
| 28 | Arc1960 | Tanzania |
| 29 | Ascension Island1958 | Ascension Island |
| 30 | Astro Beacon E 1945 | Iwo Jima |

| TM Series GNSS Receiver Supported Datums | | |
|------------------------------------------|-------------------------------|------------------------------------------------------|
| Number | Datum | Region |
| 31 | Astro Dos 71/4 | St Helena Island |
| 32 | Astro Tern Island (FRIG) 1961 | Tern Island |
| 33 | Astronomical Station 1952 | Marcus Island |
| 34 | Australian Geodetic 1966 | Australia, Tasmania |
| 35 | Australian Geodetic 1984 | Australia, Tasmania |
| 36 | Ayabelle Lighthouse | Djibouti |
| 37 | Bellevue (IGN) | Efate and Erromango Islands |
| 38 | Bermuda 1957 | Bermuda |
| 39 | Bissau | Guinea-Bissau |
| 40 | Bogota Observatory | Colombia |
| 41 | Bukit Rimpah | Indonesia (Bangka and Belitung Ids) |
| 42 | Camp Area Astro | Antarctica (McMurdi Camp Area) |
| 43 | Campo Inchauspe | Argentina |
| 44 | Canton Astro1966 | Phoenix Island |
| 45 | Cape | South Africa |
| 46 | Cape Canaveral | Bahamas, Florida |
| 47 | Carthage | Tunisia |
| 48 | Chatham Island Astro1971 | New Zealand (Chatham Island) |
| 49 | Chua Astro | Paraguay |
| 50 | Corrego Alegre | Brazil |
| 51 | Dabola | Guinea |
| 52 | Deception Island | Deception Island, Antarctica |
| 53 | Djakarta (Batavia) | Indonesia (Sumatra) |
| 54 | Dos 1968 | New Georgia Islands (Gizo Island) |
| 55 | Easter Island 1967 | Easter Island |
| 56 | Estonia Coordinate System1937 | Estonia |
| 57 | European 1950 | Cyprus |
| 58 | European 1950 | Egypt |
| 59 | European 1950 | England, Channel Islands, Scotland, Shetland Islands |
| 60 | European 1950 | England, Ireland, Scotland, Shetland Islands |
| 61 | European 1950 | Finland, Norway |
| 62 | European 1950 | Greece |
| 63 | European 1950 | Iran |

| TM Series GNSS Receiver Supported Datums | | |
|------------------------------------------|----------------------|-----------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Number | Datum | Region |
| 64 | European 1950 | Italy (Sardinia) |
| 65 | European 1950 | Italy (Sicily) |
| 66 | European 1950 | Malta |
| 67 | European 1950 | Mean For Austria, Belgium, Denmark, Finland, France, W Germany, Gibraltar, Greece, Italy, Luxembourg, Netherlands, Norway, Portugal, Spain, Sweden, Switzerland |
| 68 | European 1950 | Mean For Austria, Denmark, France, W Germany, Netherland, Switzerland |
| 69 | European 1950 | Mean For Iraq, Israel, Jordan, Lebanon, Kuwait, Saudi Arabia, Syria |
| 70 | European 1950 | Portugal, Spain |
| 71 | European 1950 | Tunisia, |
| 72 | European 1979 | Mean For Austria, Finland ,Netherlands ,Norway, Spain, Sweden, Switzerland |
| 73 | Fort Thomas 1955 | Nevis St Kitts (Leeward Islands) |
| 74 | Gan 1970 | Republic Of Maldives |
| 75 | Geodetic Datum 1970 | New Zealand |
| 76 | Graciosa Base SW1948 | Azores (Faial, Graciosa, Pico, Sao, Jorge, Terceira) |
| 77 | Guam1963 | Guam |
| 78 | Gunung Segara | Indonesia (Kalimantan) |
| 79 | Gux I Astro | Guadalcanal Island |
| 80 | Herat North | Afghanistan |
| 81 | Hermannskogel Datum | Croatia-Serbia, Bosnia-Herzegovina |
| 82 | Hjorsey 1955 | Iceland |
| 83 | Hongkong 1963 | Hong Kong |
| 84 | Hu Tzu Shan | Taiwan |
| 85 | Indian | Bangladesh |
| 86 | Indian | India, Nepal |
| 87 | Indian | Pakistan |
| 88 | Indian 1954 | Thailand |
| 89 | Indian 1960 | Vietnam (Con Son Island) |
| 90 | Indian 1960 | Vietnam (Near 16 deg N) |
| 91 | Indian 1975 | Thailand |

| TM Series GNSS Receiver Supported Datums | | |
|------------------------------------------|------------------------------|----------------------------------------|
| Number | Datum | Region |
| 92 | Indonesian 1974 | Indonesian |
| 93 | Ireland 1965 | Ireland |
| 94 | ISTS 061 Astro 1968 | South Georgia Islands |
| 95 | ISTS 073 Astro 1969 | Diego Garcia |
| 96 | Johnston Island 1961 | Johnston Island |
| 97 | Kandawala | Sri Lanka |
| 98 | Kerguelen Island 1949 | Kerguelen Island |
| 99 | Kertau 1948 | West Malaysia and Singapore |
| 100 | Kusaie Astro 1951 | Caroline Islands |
| 101 | Korean Geodetic System | South Korea |
| 102 | LC5 Astro 1961 | Cayman Brac Island |
| 103 | Leigon | Ghana |
| 104 | Liberia 1964 | Liberia |
| 105 | Luzon | Philippines (Excluding Mindanao) |
| 106 | Luzon | Philippines (Mindanao) |
| 107 | M'Poraloko | Gabon |
| 108 | Mahe 1971 | Mahe Island |
| 109 | Massawa | Ethiopia (Eritrea) |
| 110 | Merchich | Morocco |
| 111 | Midway Astro 1961 | Midway Islands |
| 112 | Minna | Cameroon |
| 113 | Minna | Nigeria |
| 114 | Montserrat Island Astro 1958 | Montserrat (Leeward Island) |
| 115 | Nahrwan | Oman (Masirah Island) |
| 116 | Nahrwan | Saudi Arabia |
| 117 | Nahrwan | United Arab Emirates |
| 118 | Naparima BWI | Trinidad and Tobago |
| 119 | North American 1927 | Alaska (Excluding Aleutian Ids) |
| 120 | North American 1927 | Alaska (Aleutian Ids East of 180 degW) |
| 121 | North American 1927 | Alaska (Aleutian Ids West of 180 degW) |
| 122 | North American 1927 | Bahamas (Except San Salvador Islands) |
| 123 | North American 1927 | Bahamas (San Salvador Islands) |

| TM Series GNSS Receiver Supported Datums | | |
|------------------------------------------|---------------------------------|------------------------------------------------------------------------------------------------------------|
| Number | Datum | Region |
| 124 | North American 1927 | Canada (Alberta, British Columbia) |
| 125 | North American 1927 | Canada (Manitoba, Ontario) |
| 126 | North American 1927 | Canada (New Brunswick, Newfoundland, Nova Scotia, Quebec) |
| 127 | North American 1927 | Canada (Northwest Territories, Saskatchewan) |
| 128 | North American 1927 | Canada (Yukon) |
| 129 | North American 1927 | Canal Zone |
| 130 | North American 1927 | Cuba |
| 131 | North American 1927 | Greenland (Hayes Peninsula) |
| 132 | North American 1927 | Mean For Antigua, Barbados, Barbuda, Caicos Islands, Cuba, Dominican, Grand Cayman, Jamaica, Turks Islands |
| 133 | North American 1927 | Mean for Belize, Costa Rica, El Salvador, Guatemala, Honduras, Nicaragua |
| 134 | North American 1927 | Mean for Canada |
| 135 | North American 1927 | Mean for Conus |
| 136 | North American 1927 | Mean for Conus (East of Mississippi, River Including Louisiana, Missouri, Minnesota) |
| 137 | North American 1927 | Mean for Conus (West of Mississippi, River Excluding Louisiana, Minnesota, Missouri) |
| 138 | North American 1927 | Mexico |
| 139 | North American 1983 | Alaska (Excluding Aleutian Ids) |
| 140 | North American 1983 | Aleutian Ids |
| 141 | North American 1983 | Canada |
| 142 | North American 1983 | Conus |
| 143 | North American 1983 | Hawaii |
| 144 | North American 1983 | Mexico, Central America |
| 145 | North Sahara 1959 | Algeria |
| 146 | Observatorio Meteorologico 1939 | Azores (Corvo and Flores Islands) |
| 147 | Old Egyptian 1907 | Egypt |
| 148 | Old Hawaiian | Hawaii |
| 149 | Old Hawaiian | Kauai |
| 150 | Old Hawaiian | Maui |

| TM Series GNSS Receiver Supported Datums | | |
|------------------------------------------|------------------------------------|--------------------------------------------------------------------|
| Number | Datum | Region |
| 151 | Old Hawaiian | Mean for Hawaii, Kauai, Maui, Oahu |
| 152 | Old Hawaiian | Oahu |
| 153 | Oman | Oman |
| 154 | Ordnance Survey Great Britain 1936 | England |
| 155 | Ordnance Survey Great Britain 1936 | England, Isle of Man, Wales |
| 156 | Ordnance Survey Great Britain 1936 | Mean For England, Isle of Man, Scotland, Shetland Island, Wales |
| 157 | Ordnance Survey Great Britain 1936 | Scotland, Shetland Islands |
| 158 | Ordnance Survey Great Britain 1936 | Wales |
| 159 | Pico de las Nieves | Canary Islands |
| 160 | Pitcairn Astro 1967 | Pitcairn Island |
| 161 | Point 58 | Mean for Burkina Faso and Niger |
| 162 | Pointe Noire 1948 | Congo |
| 163 | Porto Santo 1936 | Porto Santo, Madeira Islands |
| 164 | Provisional South American 1956 | Bolivia |
| 165 | Provisional South American 1956 | Chile (Northern Near 19 deg S) |
| 166 | Provisional South American 1956 | Chile (Southern Near 43 deg S) |
| 167 | Provisional South American 1956 | Colombia |
| 168 | Provisional South American 1956 | Ecuador |
| 169 | Provisional South American 1956 | Guyana |
| 170 | Provisional South American 1956 | Mean for Bolivia Chile, Colombia, Ecuador, Guyana, Peru, Venezuela |
| 171 | Provisional South American 1956 | Peru |
| 172 | Provisional South American 1956 | Venezuela |
| 173 | Provisional South Chilean 1963 | Chile (Near 53 deg S) (Hito XVIII) |
| 174 | Puerto Rico | Puerto Rico, Virgin Islands |
| 175 | Pulkovo 1942 | Russia |
| 176 | Qatar National | Qatar |
| 177 | Qornoq | Greenland (South) |
| 178 | Reunion | Mascarene Island |
| 179 | Rome 1940 | Italy (Sardinia) |
| 180 | S-42 (Pulkovo 1942) | Hungary |
| 181 | S-42 (Pulkovo 1942) | Poland |
| 182 | S-42 (Pulkovo 1942) | Czechoslovakia |
| 183 | S-42 (Pulkovo 1942) | Lativa |

| TM Series GNSS Receiver Supported Datums | | |
|------------------------------------------|-----------------------------|-----------------------------------------------------------------------------------------------------------------------|
| Number | Datum | Region |
| 184 | S-42 (Pulkovo 1942) | Kazakhstan |
| 185 | S-42 (Pulkovo 1942) | Albania |
| 186 | S-42 (Pulkovo 1942) | Romania |
| 187 | S-JTSK | Czechoslovakia (Prior 1 Jan1993) |
| 188 | Santo (Dos) 1965 | Espírito Santo Island |
| 189 | Sao Braz | Azores (Sao Miguel, Santa Maria Ids) |
| 190 | Sapper Hill 1943 | East Falkland Island |
| 191 | Schwarzeck | Namibia |
| 192 | Selvagem Grande 1938 | Salvage Islands |
| 193 | Sierra Leone 1960 | Sierra Leone |
| 194 | South American 1969 | Argentina |
| 195 | South American 1969 | Bolivia |
| 196 | South American 1969 | Brazil |
| 197 | South American 1969 | Chile |
| 198 | South American 1969 | Colombia |
| 199 | South American 1969 | Ecuador |
| 200 | South American 1969 | Ecuador (Baltra, Galapagos) |
| 201 | South American 1969 | Guyana |
| 202 | South American 1969 | Mean For Argentina, Bolivia, Brazil, Chile, Colombia, Ecuador, Guyana, Paraguay, Peru, Trinidad and Tobago, Venezuela |
| 203 | South American 1969 | Paraguay |
| 204 | South American 1969 | Peru |
| 205 | South American 1969 | Trinidad and Tobago |
| 206 | South American 1969 | Venezuela |
| 207 | South Asia | Singapore |
| 208 | Tananarive Observatory 1925 | Madagascar |
| 209 | Timbalai 1948 | Brunei, E Malaysia (Sabah Sarawak) |
| 210 | Tokyo | Japan |
| 211 | Tokyo | Mean for Japan, South Korea, Okinawa |
| 212 | Tokyo | Okinawa |
| 213 | Tokyo | South Korea |
| 214 | Tristan Astro 1968 | Tristam Da Cunha |
| 215 | Viti Levu 1916 | Fiji (Viti Levu Island) |

| TM Series GNSS Receiver Supported Datums | | |
|------------------------------------------|------------------------|-------------------|
| Number | Datum | Region |
| 216 | Voirol 1960 | Algeria |
| 217 | Wake Island Astro 1952 | Wake Atoll |
| 218 | Wake-Eniwetok 1960 | Marshall Islands |
| 219 | WGS 1972 | Global Definition |
| 220 | WGS 1984 | Global Definition |
| 221 | Yacare | Uruguay |
| 222 | Zanderij | Suriname |

Figure 47: Supported Datums

Resources

Support

For technical support, product documentation, application notes, regulatory guidelines and software updates, visit www.linxtechnologies.com

RF Design Services

For customers who need help implementing Linx modules, Linx offers design services including board layout assistance, programming, certification advice and packaging design. For more complex RF solutions, Apex Wireless, a division of Linx Technologies, creates optimized designs with RF components and firmware selected for the customer's application. Call +1 800 736 6677 (+1 541 471 6256 if outside the United States) for more information.

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