

JF2 Hardware User Guide

1w0300985 Rev.4 – 2013-04-09



APPLICABILITY TABLE

PRODUCT
JF2



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1. Introduction

1.1. Scope

The JF2 is an 11mm by 11mm integrated GPS receiver module using SiRFstar IV technology. This document expands upon the data sheet(s) to highlight particular areas to allow the hardware engineer to achieve a successful design implementation.

1.2. Audience

This document is intended for helping customer in the integration of the Telit SE868 GPS module.

1.3. Contact Information, Support

For general contact, technical support, to report documentation errors and to order manuals, contact Telit Technical Support Center (TTSC) at:

TS-EMEA@telit.com
TS-NORTHAMERICA@telit.com
TS-LATINAMERICA@telit.com
TS-APAC@telit.com

Alternatively, use:

<http://www.telit.com/en/products/technical-support-center/contact.php>

For detailed information about where you can buy the Telit modules or for recommendations on accessories and components visit:

<http://www.telit.com>

To register for product news and announcements or for product questions contact Telit Technical Support Center (TTSC).

Our aim is to make this guide as helpful as possible. Keep us informed of your comments and suggestions for improvements.

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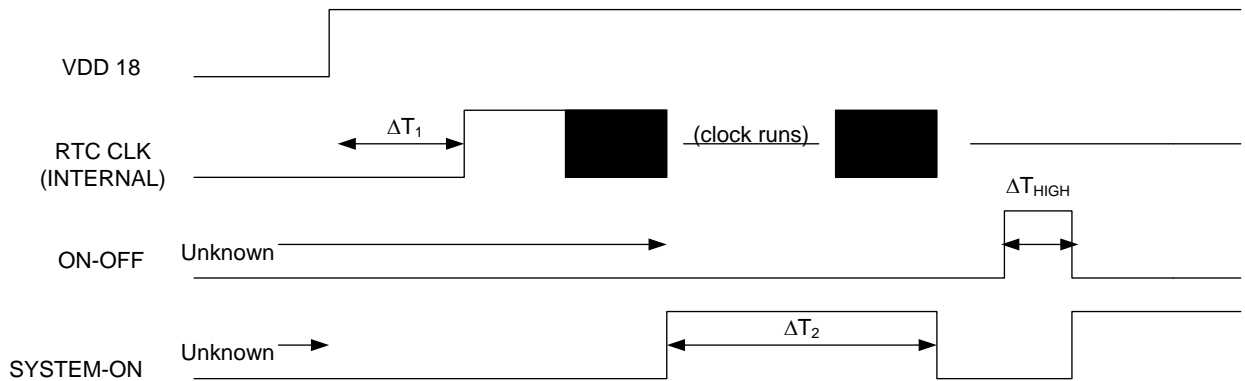


Figure 1 – Initial Application of Main Power

Timed Parameter	Prior Event/State	Symbol	Min	Typ	Max	Unit
RTC startup time	First power applied	$\square T_1$	0	299	1000	ms
FSM Ready pulse	RTC running	$\square T_2$		10		T_{RTC}
Min ON-OFF high		$\square T_{HIGH}$	3			T_{RTC}

T_{RTC} is equivalent to one RTC (32.678KHz) clock cycle.

Table 1 – Power State Timing

The host system can determine if the J-F2 is “ready” as follows

- A short pulse on SYSTEM_ON output line indicates to a host that the J-F2 is ready and armed to accept an ON_OFF pulse.
- The host can wait a fixed duration. Wait at minimum 5 seconds before sending an ON_OFF pulse. Note that Telit recommends monitoring SYSTEM_ON.
- The host can issue ON_OFF pulses repeatedly every 100ms and monitor for JF-2 SYSTEM_ON output to go HIGH. Note that issuing an ON_OFF pulse once the system is running may cause the firmware to initiate the shutdown process
- The host can issue ON_OFF repeatedly every one second and wait for serial messages to be output within the one second. Note that issuing an ON_OFF pulse once the system is running may cause the firmware to initiate the shutdown process



2.4. Reset Design Details

The JF2 NRESET pin is normally connected to a 0.33uF ceramic capacitor. The JF2 will generate an internal reset as appropriate. No external reset signal needs to be applied to the JF2.

If an external reset is desired, the signal must be either open collector or open drain without any form of pullup. Do not pull this line high with either a pullup or a driven logic one. When this line is pulled low, the JF2 will immediately drop into hibernate mode with some loss of data.

When the external reset is released, the JF2 will go through its normal power up sequence provided the VCC_IN supply is within specifications.



3. Example Implementations

This section illustrates the implementations that meet the rules for the JF2. Telit recommends assessing the risks when making implementation decisions

3.1. Normal Operation Startup and Shutdown

To start the JF2:

Send a voltage pulse (tolerant to 3.6V) to the ON-OFF input.

To go into the shutdown sequence of the JF2 from full power state :

Send a voltage pulse (tolerant to 3.6V) to the ON-OFF input

or

Issue an NMEA (\$PSRF117) or OSP (MID 205) serial command.

3.2. Self-Start Operation

For self-start operation, the SYSTEM-ON output is connected to the ON-OFF input. The JF2 then goes into full power run state when the supply voltage is first applied. GPIO8 must be pulled HIGH in this case to set the ON-OFF input to an ON only signal.



4. Updating the Firmware: Flash Module (ONLY)

During normal operations, the BOOT signal should be tied to ground through a 100K pulldown resistor. This will ensure the GPS module executes the code out of the internal flash memory.

However, if the internal flash memory needs to be updated, the following steps should be performed to place the JF2 module into a state suitable for programming the internal flash memory.

1. Either remove all power to the module, or force the module into hibernate state by pulsing the ON-OFF signal. Verify the state of the module by monitoring the SYSTEM-ON signal.
2. Pull the BOOT signal high through a 10K pull up resistor to +1.8 volts.
3. Apply main power if not already applied.
4. Pulse the ON-OFF signal to place the JF2 module into BOOT mode.
5. Run the software utility to re-flash the JF2 module. Clearing the entire flash memory is strongly recommended prior to programming.
6. Upon successful completion of re-flashing, remove main power to the module for a minimum of 10 seconds.
7. Pull the BOOT signal low through a 100K pull down resistor to GND.
8. Apply main power to the JF2.
9. Pulse the ON-OFF signal to place the JF2 into the normal operating state.



7. Main Serial Interface

The JF2 has the capability to operate in serial UART mode, SPI mode or I2C mode depending upon how the JF2 GPIO6 and GPIO7 pins are strapped at power up. Either leave the pin floating, apply a 10K resistor to +1.8V (PU) or apply a 10K resistor to GND (PD). Reference the JF2 SPI_UART_I2C Application Note for additional details on Serial Interface configuration and operation.

Mode	GPIO6 (internal pull-down)	GPIO7 (internal pull-up)
UART	PU	Leave floating or PU
I2C	Leave floating or PD	PD
SPI	Leave floating	Leave floating

Table 3 – Interface Operating Modes



8. MEMS Sensor/EEPROM Interface

The DR I2C port is used for connecting to MEMS sensors, such as accelerometer or magnetometer. Pullup resistors of approximately 2.2Kohm to 1.8 volts are required on the DR I2C CLK and DR I2C IO lines for proper operation.

Only an approved accelerometer (KIONIX part number KXTF9-4100, 3 x 3mm LGA 1.8V 3 axis accelerometer and FREESCALE part number MMA8450Q) can be used. The interrupt output of the accelerometer must be connected to GPIO4 of the JF2.

Data for the approved magnetic sensor (Aichi Steel part number AIM304, 3.5 x 4.0mm 3V 3 axis magnetometer) is output in OSP message 72.



9. RF Front End Design

The JF2 contains an integrated LNA and pre-select SAW filter. This allows the JF2 to work well with a passive GPS antenna. If the antenna cannot be located near the JF2, then an active antenna (that is, an antenna with a low noise amplifier built in) can be used. The following items will be discussed in turn to assist in designing the “RF front end”.

1. RF signal requirements
2. GPS antenna polarization
3. GPS antenna gain
4. System noise floor
5. Active versus passive antenna
6. RF trace losses
7. Implications of the pre-select SAW filter
8. External LNA gain and Noise Figure
9. Powering the external LNA (active antenna)
10. RF interference
11. Shielding

9.1. RF Signal Requirements

The JF2 can achieve Cold Start acquisition with a signal level of -147 dBm at its input. This means the JF2 can find the necessary satellites, download the necessary ephemeris data and compute the location within a 5 minute period. In the GPS signal acquisition process, downloading and decoding the data is the most difficult task, which is why Cold Start acquisition requires a higher signal level than navigation or tracking signal levels. For the purposes of this discussion, autonomous operation is assumed, which makes the Cold Start acquisition level the important design constraint. If assistance data in the form of time or ephemeris aiding is available, then even lower signal levels can be used to compute a navigation solution.

The GPS signal is defined by IS-GPS-200E. This document states that the signal level received by a linearly polarized antenna having 3 dBi gain will be a minimum of -130 dBm when the antenna is in the worst orientation and the satellite is 5 degrees or more above the horizon.

In actual practice, the GPS satellites are outputting slightly more power than specified by IS-GPS-200E, and the signal level typically goes higher as the satellites have higher elevation angles.

The JF2 will display a reported C/No of 40 dB-Hz for a signal level of -130 dBm into the RF input.



Each GPS satellite presents its own signal to the JF2, and best performance is obtained when the signal levels are between -125 dBm and -117 dBm. These received signal levels are determined by

- GPS satellite transmit power
- GPS satellite elevation and azimuth
- Free space path loss
- Extraneous path loss such as rain
- Partial or total path blockage such as foliage or building
- Multipath caused by signal reflection
- GPS antenna
- Signal path after the GPS antenna

The first three items in the list above are specified in IS-GPS-200E, readily available multiple sources online. IS-GPS-200E specifies a signal level minimum of -130 dBm will be presented to the receiver when using a linearly polarized antenna with 3 dBi gain.

The GPS signal is relatively immune to rainfall attenuation and does not really need to be considered.

However, the GPS signal is heavily influence by attenuation due to foliage, such as tree canopies, etc. as well as outright blockage caused by building, terrain or other items in the line of sight to the specific GPS satellite. This variable attenuation is highly dependent upon GPS satellite location. If enough satellites are blocked, say at a lower elevation, or all in a general direction, the geometry of the remaining satellites will result is a lower accuracy of position. The JF2 reports this geometry in the form of PDOP, HDOP and VDOP.

For example, in a vehicular application, the GPS antenna may be placed embedded into the dashboard or rear package tray of an automobile. The metal roof of the vehicle will cause significant blockage, plus any thermal coating applied to the vehicle glass can attenuate the GPS signal by as much as 15 dB. Again, both of these factors will affect the performance of the receiver.

Multipath is a phenomena where the signal from a particular satellite is reflected and is received by the GPS antenna in addition to or in place of the original line of sight signal. The multipath signal has a path length that is longer than the original line of sight path and can either attenuate the original signal, or if received in place of the original signal add additional error is determining a solution because the distance to the particular GPS satellite is actually longer than expected. It is this phenomena that makes GPS navigation in urban canyons (narrow roads surround by high rise buildings) so challenging. In general, the reflecting of the GPS signal causes the polarization to reverse. The implications of this are covered in the next section.



9.2. GPS Antenna Polarization

The GPS signal as broadcast is a right hand circularly polarized signal. The best antenna to receive the GPS signal is a right hand circularly (RHCP) polarized antenna. Remember that IS-GPS-200E specifies the receive power level with a linearly polarized antenna. A linearly polarized antenna will have 3 dB loss as compared to an RHCP antenna assuming the same antenna gain (specified in dBi and dBic respectively).

An RHCP antenna is better at rejecting multipath than a linearly polarized antenna. This is because the reflected signal changes polarization to LHCP, which would be rejected by the RHCP antenna by typically 20 dB or so. If the multipath signal is attenuating the line of sight signal, then the RHCP antenna would show a higher signal level than a linearly polarized antenna because the interfering signal is rejected.

However, in the case where the multipath signal is replacing the line of sight signal, such as in an urban canyon environment, then the number of satellites in view could drop below that needed to determine a 3D solution. This is a case where a bad signal may be better than no signal. The system designer needs to make tradeoffs in their application to determine what is the better choice.

9.3. GPS Antenna Gain

Antenna gain is defined as the extra signal power from the antenna as compared to a theoretical isotropic antenna (equally sensitive in all directions).

For example, a 25mm by 25mm square patch antenna on a reference ground plane (usually 70mm by 70mm) will give an antenna gain at zenith of 5 dBic. A smaller 18mm by 18mm square patch on a reference ground plane (usually 50mm by 50mm) will give an antenna gain at zenith of 2 dBic.

While an antenna vendor will specify a nominal antenna gain (usually at zenith, or directly overhead) they should supply antenna pattern curves specifying gain as a function of elevation, and gain at a fixed elevation as a function of azimuth. Pay careful attention to the requirement to meet these specifications, such as ground plane required and any external matching components. Failure to follow these requirements could result in very poor antenna performance.

It is important to note that GPS antenna gain is not the same thing as external LNA gain. Most antenna vendors will specify these numbers separately, but some combine them into a single number. It is important to know both numbers when designing and evaluating the front end of a GPS receiver.

For example, antenna X has an antenna gain of 5 dBic at azimuth and an LNA gain of 20 dB for a combined total of 25 dB. Antenna Y has an antenna gain of -5 dBic at azimuth and an LNA gain of 30 dB for a combined total of 25 dB. However, in the system, antenna X will outperform antenna Y by about 10 dB (refer to Section 9.4 for more details on system noise floor).

An antenna with higher gain will generally outperform an antenna with lower gain. Once the signals are above about -130 dBm for a particular satellite, no improvement in performance would be gained. However, for those satellite that are below about -125 dBm, a higher gain antenna would improve the gain and improve the performance of the GPS receiver. In the case of really weak signals, a good antenna could mean the difference between being able to use a particular satellite signal or not.



9.4. System Noise Floor

As mentioned earlier, the JF2 will display a reported C/No of 40 dB-Hz for an input signal level of -130 dBm. The C/No number means the carrier (or signal) is 40 dB greater than the noise floor measured in a one Hz bandwidth. This is a standard method of measuring GPS receiver performance.

Thermal noise is -174 dBm/Hz at around room temperature. From this we can compute a system noise figure of 4 dB for the JF2. This noise figure consists of the loss of the pre-select SAW filter, the noise figure of the LNA as well as implementation losses within the digital signal processing unit.

If a good quality external LNA is used with the JF2, then the noise figure of that LNA (typically better than 1dB) could reduce the overall system noise figure of the JF2 from 4 dB to around 2 dB. Some of the factors in the system noise figure are implementation losses due to quantization and other factors and don't scale with improved front end noise figure.

9.5. Active versus Passive Antenna

If the GPS antenna is placed near the JF2 and the RF traces losses are not excessive (nominally 1 dB), then a passive antenna can be used. This would normally be the lowest cost option and most of the time the simplest to use. However, if the antenna needs to be located away from the JF2 then an active antenna may be required to obtain the best system performance. The active antenna has its own built in low noise amplifier to overcome RF trace or cable losses after the active antenna.

However, an active antenna has a low noise amplifier (LNA) with associated gain and noise figure. In addition, many active antenna have either a pre-select filter, a post-select filter or both.

9.6. RF Trace Losses

RF Trace losses are difficult to estimate on a PCB without having the appropriate tables or RF simulation software to estimate what the losses would be. A good rule of thumb would be to keep the RF traces as short as possible, make sure they are 50 ohms impedance and don't contain any sharp bends.



9.7. Implications of the Pre-select SAW Filter

The JF2 module contains a SAW filter used in a pre-select configuration with the built in LNA, that is the RF input of the JF2 ties directly into the SAW filter. Any circuit connected to the input of the JF2 would see a complex impedance presented by the SAW filter, particularly out of band, rather than the relatively broad and flat return loss presented by the LNA. Filter devices pass the desired in band signal to the output, resulting in low reflected energy (good return loss), and reject the out of band signal by reflecting it back to the input, resulting in high reflected energy (bad return loss).

If an external amplifier is to be used with the JF2, the overall design should be checked for RF stability to prevent the external amplifier from oscillating. Amplifiers that are unconditionally stable at the output will be fine to use with the JF2.

If an external filter is to be connected directly to the JF2, care needs to be used in making sure neither the external filter or the internal SAW filter performance is compromised. These components are typically specified to operate into 50 ohms impedance, which is generally true in band, but would not be true out of band. If there is extra gain associated with the external filter, then a 6 dB Pi or T resistive attenuator is suggested to improve the impedance match between the two components.

9.8. External LNA Gain and Noise Figure

The JF2 can be used with an external LNA such as what might be found in an active antenna. Because of the internal LNA, the overall gain (including signal losses past the external LNA) should not exceed 14 dB. Levels higher than that can affect the jamming detection capability of the JF2. If a higher gain LNA is used, either a resistive Pi or T attenuator can be inserted after the LNA to bring the gain down to 14 dB or the JF2 can be switched into a low gain mode by issuing an OSP command to do so.

The external LNA should have a noise figure better than 1 dB. This will give an overall system noise figure of around 2 dB assuming the LNA gain is 14 dB, or if higher the low gain mode is selected within the JF2.

The external LNA, if having no pre-select filter, needs to be able to handle other signals other than the GPS signal. These signals are typically at much higher levels. The amplifier needs to stay in the linear region when presented with these other signals. Again, the system designer needs to determine all of the unintended signals and their possible levels that can be presented and make sure the external LNA will not be driven into compression. If this were to happen, the GPS signal itself would start to be attenuated and the GPS performance would suffer.



9.10. RF Interference

RF Interference into the GPS receiver tends to be the biggest problem when determining why the system performance is not meeting expectations. As mentioned earlier, the GPS signals are at -130 dBm and lower. If signal higher than this are presented to the receiver it can be overwhelmed. The JF2 can reject up to 8 CW in-band jamming signals, but would still be affected by non-CW signals.

The most common source of interference is digital noise. This is created by the fast rise and fall times and high clock speeds of modern digital circuitry. For example, a popular netbook computer uses an Atom processor clocked at 1.6 GHz. This is only 25 MHz away from the GPS signal, and depending upon temperature of the SAW filter, can be within the passband of the GPS receiver. Because of the nature of the address and data lines, this would be broadband digital noise at a relatively high level.

Such devices are required to adhere to a regulatory standard for emissions such as FCC Part 15 Subpart J Class B or CISPR 22. However, these regulatory emission levels are far higher than the GPS signal.

9.11. Shielding

Shielding the RF circuitry generally is ineffective because the interference is getting into the GPS antenna itself, the most sensitive portion of the RF path. The antenna cannot be shielded because then it can't receive the GPS signals.

There are two solutions, one is to move the antenna away from the source of interference or the second is to shield the digital interference to prevent it from getting to the antenna.



10.2. ROM2.2 9600bps

The JF2 ROM2.2 9600bps variant does not support external EEPROM connection or MEMS connection. Note that if a SPI flash is connected, the baud rate defaults to 4800.



11. Firmware Configuration

The JF2 can be configured by means of firmware in order to fit better into the overall system. This section describes certain aspects of the receiver that can be configured.

11.1. Internal LNA

The JF2 offers two modes of operation, high gain mode and low gain mode, for the internal LNA. The high gain mode is the default mode and provides 16 to 20dB of gain. The low gain mode provides 6 to 10dB of gain.

In general, the high gain mode is intended for use with passive antennas, while the low gain mode is used when there is an external LNA as part of the RF front end (e.g. active antenna). The recommended external LNA gain is 20dB.

A version of JF2 firmware is offered for system designs that require the low LNA gain mode. The gain mode is set by the firmware when the receiver starts up. The Tracker Config message (OSP MID178, SID2) can also be used to change the LNA mode, but note that the use of this message is not recommended, because an incorrect parameter could render the JF2 inoperable. Contact Telit technical support if this approach is required in your system.

11.2. Low Power Modes

The JF2 module can be operated in one of four power management modes; Full Power, TricklePower™, Push-To-Fix™, and Micro Power. The latter three of these modes offer progressively lower power consumption profiles. Depending upon the requirements of the system design regarding frequency of position updates and availability of GPS signals in the operational environment, the designer can choose a mode that provides the best trade-off of performance versus power consumption.

Each of the power management modes can be commanded using the Power Mode Request Message (MID218), which is available as part of the OSP message set. More details regarding low power operation can be found in the Low Power Operating Modes Application Note.

11.2.1. Full Power

This mode consumes the most average power, but it is the most accurate navigation mode and supports the most dynamic motion scenarios.

11.2.2. TricklePower™

This mode is a duty-cycling mode. It provides navigation updates at a fixed rate and retains a high quality of GPS accuracy and dynamic motion response, but at a lower average power cost as compared to Full Power operation. TricklePower mode produces significant power savings in strong signal conditions.



11.2.3. Push-To-Fix

This mode provides for even lower power consumption than TricklePower. It is intended for applications that require infrequent position reports. The position is reported periodically by the receiver (once every 30 minutes by default) and also when requested. To request a position update, a pulse is asserted on the ON-OFF pin.

11.2.4. Micro Power Mode (MPM)

Micro Power mode is the lowest power operating mode. Rather than providing position updates at a reduced rate, it is predicated on maintaining the availability of a navigation solution by maintaining hot start conditions in the receiver at all times. The receiver is put into Full Power by pulsing the ON-OFF pin. It is put back into Micro Power mode by sending a Power Mode Request command to the receiver.

11.3. Host Serial Interface

As mentioned above in Section 7, the host serial interface can be configured as a UART, I2C or SPI port by strapping one or both pins GPIO 6 and GPIO 7 to certain levels at power up. The data rate for I2C is fixed at 400 kbps. The slave SPI supports a maximum clock input rate of 6.8 MHz. The UART can operate at baud rates of 4800, 9600, 19200, 38400, 57600, 115200, 230400 and 460800 bps.

11.3.1. NMEA Protocol Considerations

The lower UART baud rates are typically used for NMEA protocol. Note should be taken however of the bandwidth limitation at 4800 baud. By default, the JF2 module communicates using NMEA at 4800 baud, with the periodic output messages limited to the GGA, GSA and RMC messages at once per second and the GSV message once every five seconds. At 9600 baud or higher, additional output messages may be enabled.

If the JF2 is operated in TricklePower mode, a baud rate of at least 38400 is recommended. This reduces the time required for data output and allows the receiver to drop into the lowest power state for a longer average time.

Use the Set Serial Port (PSRF100) NMEA command to change the baud rate. This command can also be used to switch the protocol to OSP as described in the next section. Use the Query/Rate Control (PSRF103) to enable and disable output messages and set their output rates.

11.3.2. OSP Considerations

The higher baud rates are used for OSP. OSP offers a richer set of commands and more types of data output than does NMEA. Use the Set Serial Port (PSRF100) NMEA command to switch the protocol from NMEA to OSP. The minimum recommended baud rate for OSP is 38400, provided that debug data messages are not enabled. If data debug messages are enabled, the minimum baud rate is 115200 in order to prevent data from being dropped. The protocol can be switched back to NMEA using the Switch to NMEA Protocol command (Message ID 129).



11.4. MEMS Configuration

The JF2 module interfaces to MEMS sensors using the dead reckoning (DR) I2C bus as mentioned in Section 8. The sensors that may be connected are an accelerometer and a magnetometer, also called a digital compass.

A Sensor Configuration OSP message (Message ID 234, Sub ID 1) must be sent to the JF2 in order to configure it to interface with the connected sensor or sensors. The configuration data in this message is extensive and is described in detail in the OSP Manual. After the sensor interface has been configured, the sensors must be enabled using the Sensor Switch message (Message ID 234, Sub ID 2).

Once the sensor interface has been configured and the sensors enabled, the sensor data will be output by the JF2 in OSP Message 72, Sub ID 1. Note that a data message is output for each sensor and can contain several sets of data from the given sensor.

The JF2 ROM2.2 9600 version does not support MEMS.

11.5. Motion Dynamics

11.5.1. Static Navigation

Static navigation, also called position pinning, is a mechanism that it is used by the receiver to freeze, or pin, the position when the velocity falls below a threshold indicating that the receiver is stationary. The heading is also frozen, and the velocity is reported as 0. The solution is then unpinned when the velocity increases above a threshold or when the computed position is a set distance from the pinned position, indicating that the receiver is in motion again. Note that these velocity and distance thresholds cannot be changed.

By default static navigation is disabled. It can be enabled by sending a Static Navigation message (Message ID 143) with the static navigation flag set to 1. This feature is useful for applications in which very low dynamics are not expected, the classic example being an automotive application.

11.5.2. Velocity Dead-Reckoning

Velocity dead-reckoning refers to the use of the last known velocity to propagate the navigation solution when there are insufficient measurements to calculate an updated solution. It serves to mitigate the effects of blocked satellite signals by continuing to provide a position output. Note that the receiver outputs status information which indicates whether a solution is being maintained using dead-reckoning.

By default the receiver operates in dead-reckoning mode for up to 15 seconds before invalidating the position. This timeout value is considered to be appropriate for most applications. It can be changed using the Mode Control message (Message ID 136). Valid timeout values are in a range from zero, which disables dead-reckoning, to two minutes.



11.5.3. MEMS Static Detection

MEMS Static Detection uses 3-axis accelerometer data to constrain position drifts and wander during stationary periods of operation.

MEMS Static Detection is an improvement over the Static Navigation method because the accuracy of the accelerometer data is not a function of the dynamics of the receivers or the signal level of the GPS satellites.

11.5.4. MEMS Wake-up

MEMS Wake-up also uses a 3-axis accelerometer to determine if the receiver is moving or not. Currently this is only a sub-feature of MPM, not a stand-alone feature.

In this feature, an acceleration threshold is programmed into the actual sensor device. If the programmed threshold is exceeded, the interrupt output from the accelerometer device becomes active.

If MPM is in a degraded mode (lack of signal acquisition during the periodic update cycles) and the software is configured to allow sensor wakes, the MEMS Wake-up will attempt more frequent calibration cycles, under the assumption that movement of the receiver may result in different and/or better signal conditions.

11.6. Advanced Features

11.6.1. CW Jamming Detection

The JF2 module detects, tracks and removes narrow-band interfering signals (jammers) without the need for external components or tuning. It monitors a frequency band that is +/- 4MHz from the L1 frequency for jammers. Any number of jammers that occur outside of a +/-1MHz center band are removed by the JF2 with a 2MHz band pass filter. Up to eight jammers inside this center band are removed using a notch filter.

Data regarding detected jammers is output using OSP messages. Message ID 92, Sub ID 1, reports up to eight of the most recently detected interferers. This feature is useful both in the design stage and during the production stage for uncovering issues related to unexpected jamming.

11.6.2. SBAS

The JF2 receiver is capable of using Satellite-Based Augmentation System (SBAS) satellites as a source of both differential corrections and satellite range measurements. These systems (WAAS, EGNOS, MSAS) use geostationary satellites to transmit regional differential corrections via a GPS-compatible signal. The use of SBAS corrections can improve typical position accuracy to 3m or less in open-sky applications.

Note that only an SBAS can be used as source of differential corrections. Other sources such as data from RTCM beacons are not supported.

By default the JF2 does not attempt to acquire SBAS satellites. This can be changed by sending in a DGPS Source command (MID 133) and specifying the source of DGPS corrections as SBAS. When the receiver acquires SBAS satellites, it will demodulate and use corrections data from the satellite signal.



The receiver can be configured to compute SBAS satellite range measurements and use them in the navigation solution. This can be enabled through a control bit in the OSP Mode Control command (MID 136). See the OSP Manual for details.

11.6.3. 2-D Acquisition

By default, the JF2 will compute a 2-D solution when possible when performing initial acquisition. In a 2-D solution, the receiver assumes a value for altitude and uses it to estimate the horizontal position. Under warm and hot start conditions, the receiver uses the last known value of altitude, which is a good assumption in most situations.

However under cold start conditions, the last position is unknown, and the receiver assumes a value of 0. In situations where the true altitude is significantly higher than that, the horizontal position estimate will be noticeably impacted. To accommodate applications for which these situations are a concern, a version of JF2 firmware is offered that requires a calculated altitude, i.e. a 3-D navigational solution, in order for the receiver to first enter navigation.

11.6.4. MEMS Compass Heading

The JF2 module incorporates a feature that reads and reports the compass heading from a 3-axis magnetometer. The raw heading data is used to enhance navigation performance under low speed conditions. The raw heading data is also reported over the OSP message interface. The compass heading information meets the following general performance guidelines:

- 50% Heading Accuracy 2 Deg
- 95% Heading Accuracy 5 Deg

NOTE: The magnetic compass feature and performance is affected by the magnetic environment due to magnetic anomalies. These can typically be caused by large masses of ferrous metal, such as iron, as well as natural disturbances in the earth's magnetic field. These magnetic anomalies cause errors in the sensing of the magnetic field and result in larger than specified errors.



12. Handling and soldering

12.1. Moisture Sensitivity

The JF2 module has a moisture sensitivity level rating of 3 as defined by IPC/JEDEC J-STD-020. This rating is assigned due to some of the components used within the JF2.


The JF2 is supplied in trays or tape and reel and is hermetically sealed with desiccant and humidity indicator card. The JF2 parts must be placed and reflowed within 168 hours of first opening the hermetic seal provided the factory conditions are less than 30°C and less than 60% and the humidity indicator card indicates less than 10% relative humidity.

If the package has been opened or the humidity indicator card indicates above 10%, then the parts will need to be baked prior to reflow. The parts may be baked at $+125^{\circ}\text{C} \pm 5^{\circ}\text{C}$ for 48 hours. However, the trays, nor the tape and reel can withstand that temperature. Lower temperature baking is feasible if the humidity level is low and time is available. Please see IPC/JEDEC J-STD-033 for additional information.

Additional information can be found on the MSL tag affixed to the outside of the hermetical seal bag.

NOTE:

JEDEC standards are available for free from the JEDEC website <http://www.jedec.org>.



CAUTION
This bag contains
MOISTURE-SENSITIVE DEVICES

LEVEL

3

If Blank, see adjacent bar code label

1. Calculated shelf life in sealed bag: 12 months at $< 40^{\circ}\text{C}$ and $< 90\%$ relative humidity (RH)
2. Peak package body temperature: _____ $^{\circ}\text{C}$
If Blank, see adjacent bar code label
3. After bag is opened, devices that will be subjected to reflow solder or other high temperature process must
 - a) Mounted within: 168 hours of factory
If Blank, see adjacent bar code label
conditions $\leq 30^{\circ}\text{C}/60\%$
 - b) stored at $<10\%$ RH
4. Devices require bake, before mounting, if:
 - a) Humidity Indicator Card is $> 10\%$ when read at $23 \pm 5^{\circ}\text{C}$
 - b) 3a or 3b not met.
5. If baking is required, devices may be baked for 48 hours at $125 \pm 5^{\circ}\text{C}$

Note: If device containers cannot be subjected to high temperature or shorter bake times are desired, reference IPC/JEDEC J-STD-033 for bake procedure

Bag Seal Date: _____
If Blank, see adjacent bar code label

Note: Level and body temperature defined by IPC/JEDEC J-STD-020

Figure 3 Label for Moisture Sensitive Devices



12.2. ESD

The JF2 is an electrostatic discharge sensitive device and should be handled in accordance with JESD625-A requirements for Handling Electrostatic Discharge Sensitive (ESDS) Devices. Although the JF2 is a module, the expected handling of the JF2 during assembly and test is identical to that of a semiconductor device.

Note: JEDEC standards are available for free from the JEDEC website <http://www.jedec.org>.

12.3. Reflow

The JF2 is compatible with lead free soldering processes as defined in IPC/JEDEC J-STD-020. The reflow profile must not exceed the profile given IPC/JEDEC J-STD-020 Table 5-2, "Classification Reflow Profiles". Although IPC/JEDEC J-STD-020 allows for three reflows, the assembly process for the JF2 uses one of those profiles. Thus the JF2 is limited to two reflows.

Note: JEDEC standards are available for free from the JEDEC website <http://www.jedec.org>. When reflowing a dual-sided SMT board, it is important to reflow the side containing the JF2 module last. This prevents heavier components within the JF2 becoming dislodged if the solder reaches liquidus temperature while the module is inverted.

12.4. Assembly Issues

Due to the piezo-electric components within the JF2, the component should be placed close to the end of the assembly process to minimize shock to the module. During board singulation, pay careful attention to unwanted vibrations and resonances introduced into the board assembly by the board router.



14. Document History

Revision	Date	Changes
0	2011-01-19	First issue
1	2012-11-14	Made corrections for Figure 2
2	2012-11-29	Added ON_OFF notes in section 2.3 and update Figure 4 and 10.1
3	2013-03-19	Updated ON-OFF section and added ROM2.2 features
4	2013-04-05	Update section 10 Reference Design and remove Baud Rate Detection

