

# PwrPak7D-E2

## OEM7 Dual Antenna Enclosure With SPAN GNSS+INS Technology Provides Improved Performance And Higher Data Rates



### Dual Antenna Input

Multi-frequency, dual antenna input allows the PwrPak7D-E2 to harness the power of RTK and ALIGN functionality. This makes the PwrPak7D-E2 ideal for ground, marine or aircraft based systems, providing industry-leading GNSS multi-constellation heading and position data in static and dynamic environments.

### World Leading GNSS+INS Technology

SPAN GNSS+INS technology brings together two different but complementary technologies: Global Navigation Satellite System (GNSS) positioning and Inertial Navigation System (INS). The absolute accuracy of GNSS positioning and the stability of Inertial Measurement Unit (IMU) gyro and accelerometer measurements are deeply coupled to provide an exceptional 3D navigation solution that is stable and continuously available, even through periods when satellite signals are blocked.

### SPAN-Enabled MEMS Receiver

The PwrPak7D-E2 contains an Epson G370N MEMS IMU to deliver world class SPAN technology by Hexagon | NovAtel in an integrated, single box solution. Built on top of the reputable PwrPak7 family, with a higher performance Epson IMU, it provides seamless positioning, quick alignment and excellent performance. This product is commercially exportable and provides an excellent midrange price/performance/size GNSS+INS solution.

### Future-Proofed Scalability

Capable of tracking all present and upcoming GNSS constellations and satellite signals, the PwrPak7D-E2 is a robust, high-precision receiver that is software upgradeable in the field to provide the custom performance required for your application demands.

The PwrPak7D-E2 has a powerful OEM7 GNSS engine, integrated MEMS IMU, built in Wi-Fi, onboard NTRIP client and server support, and 16 GB of internal storage.

### Precise Thinking Makes It Possible

Our GNSS products have set the standard in quality and performance for over 20 years. State-of-the-art, lean manufacturing facilities in our North American headquarters produce the industry's most extensive line of OEM receivers, antennas and subsystems.

### Benefits

- Small, low-power, all-in-one GNSS+INS enclosure
- Easy integration into space and weight constrained applications
- Commercially exportable system
- Rugged design ideal for challenging environments
- Enhanced connection options including serial, USB, CAN and Ethernet
- Future-proof for upcoming GNSS signal support

### Features

- Low noise commercial grade Gyros and Accelerometers
- Dedicated Wheel Sensor input
- TerraStar correction services supported over multi-channel L-Band and IP connections
- Advanced interference mitigation features
- SPAN GNSS+INS capability with configurable application profiles
- Dual antenna ALIGN heading
- 16 GB of internal storage
- Built-in Wi-Fi support

**Performance** <sup>1</sup>

**Signal Tracking** <sup>2</sup>

GPS L1 C/A, L1C, L2C, L2P, L5  
 GLONASS <sup>3</sup> L1 C/A, L2 C/A, L2P, L3, L5

Galileo <sup>4</sup> E1, E5 AltBOC, E5a, E5b  
 BeiDou B1I, B1C, B2I, B2a, B2b  
 QZSS L1 C/A, L1C, L2C, L5

NavIC (IRNSS) L5  
 SBAS <sup>5</sup> L1, L5  
 L-Band <sup>5</sup> up to 5 channels

**Horizontal Position Accuracy (RMS)**

Single Point L1 1.5 m  
 Single Point L1/L2 1.2 m  
 SBAS <sup>6</sup> 60 cm  
 DGPS 40 cm  
 TerraStar-L <sup>7</sup> 40 cm  
 TerraStar-C PRO <sup>7</sup> 2.5 cm  
 TerraStar-X <sup>7</sup> 2 cm  
 RTK 1 cm + 1 ppm  
 Initialization time < 10 s  
 Initialization reliability > 99.9%

**ALIGN Heading Accuracy**

Baseline Accuracy (RMS)  
 2 m 0.08 deg  
 4 m 0.05 deg

**Maximum Data Rate**

GNSS Measurements up to 20 Hz  
 GNSS Position up to 20 Hz  
 INS Solution up to 200 Hz  
 IMU Raw Data Rate 200 Hz

**Time to First Fix**

Cold start <sup>8</sup> < 39 s (typ)  
 Hot start <sup>9</sup> < 20 s (typ)

**Time Accuracy** <sup>10</sup> 20 ns RMS

**Velocity Limit** <sup>11</sup> 515 m/s

**IMU Performance** <sup>12</sup>

**Gyroscope Performance**

Input range ±450 deg/s  
 Rate bias stability 0.8 deg/hr  
 Angular random walk 0.06 deg/√hr

**Accelerometer Performance**

Range ±10 g  
 Bias stability 0.01 mg  
 Velocity random walk 0.025 m/s/√hr

**Communication Ports**

1 RS-232 up to 460,800 bps  
 2 RS-232/RS-422 selectable up to 460,800 bps

1 USB 2.0 (device) HS  
 1 USB 2.0 (host) HS  
 1 Ethernet 10/100 Mbps  
 1 CAN Bus 1 Mbps  
 1 Wi-Fi  
 3 Event inputs  
 3 Event outputs  
 1 Pulse Per Second output  
 1 Quadrature Wheel Sensor input

**Physical and Electrical**

Dimensions 147 x 125 x 55 mm

Weight 560 g

**Power**

Input voltage +9 to +36 VDC  
 Power consumption <sup>13</sup> 4.15 W

**2 Antenna LNA Power Outputs**

Output voltage 5 VDC ±5%  
 Maximum current 200 mA

**Connectors**

2 Antenna SMA  
 USB device Micro A/B  
 USB host Micro A/B  
 Serial, CAN, Event I/O DSUB HD26  
 Ethernet RJ45  
 Data Logging Push button  
 Power SAL M12, 5 pin, male

**Status LEDs**

Power  
 GNSS  
 INS  
 Data Logging  
 USB

**Environmental**

**Temperature**

Operating -40°C to +75°C  
 Storage -40°C to +85°C

**Humidity** 95% non-condensing

**Ingress Protection Rating** IP67

**Vibration (operating) Random**

MIL-STD-810H, Method 514.8  
 Profiles:

- Rail CAT 11 – 0.5 g RMS
- Composite Wheeled Vehicle CAT 4 – 2.24 g RMS
- Aircraft Propeller CAT 13 – 4.5 g RMS

**Acceleration (operating)**

MIL-STD-810H, Method 513.8  
 Procedure II (16 g)

**Bump (operating)**

IEC 60068-2-27 (25g)

**Shock (operating)** <sup>14</sup>

MIL-STD-810H, Method 516.8, Procedure 1, 40 g 11 ms terminal sawtooth

**Compliance**

FCC, ISED, CE and Global Type Approvals

**Included Accessories**

- Power cable
- USB cable
- DSUB HD26 to DB9 RS-232 cable

**Optional Accessories**

- Full breakout cable for DSUB HD26 connector
- DSUB HD26 to M12 IMU cable
- RJ45 Ethernet cable
- VEXXIS GNSS-500 and GNSS -800 series antennas
- Compact GNSS antennas
- GrafNav/GrafNet
- Inertial Explorer
- NovAtel Application Suite

**Hardware Options**

PwrPak7DQ-E2 no Wi-Fi

**Performance During GNSS Outages** <sup>1</sup>

Outage Duration	Positioning Mode	Position Accuracy (M) RMS		Velocity Accuracy (M/S) RMS		Attitude Accuracy (Degrees) RMS		
		Horizontal	Vertical	Horizontal	Vertical	Roll	Pitch	Heading
0 s	RTK <sup>15</sup>	0.02	0.03					
	PPP	0.06	0.15	0.015	0.010	0.013	0.013	0.070
	SP	1.00	0.60					
	Post Processed <sup>16</sup>	0.01	0.02	0.015	0.010	0.005	0.005	0.010
10 s	RTK <sup>15</sup>	0.17	0.13					
	PPP	0.21	0.25	0.040	0.020	0.022	0.022	0.085
	SP	1.15	0.70					
	Post Processed <sup>16</sup>	0.02	0.02	0.015	0.010	0.005	0.005	0.010
60 s	RTK <sup>15</sup>	5.02	1.03					
	PPP	5.06	1.15	0.220	0.035	0.035	0.035	0.120
	SP	6.00	1.60					
	Post Processed <sup>16</sup>	0.17	0.06	0.017	0.010	0.005	0.005	0.012

1. Typical values. Performance specifications subject to GNSS system characteristics, Signal-in-Space (SIS) operational degradation, ionospheric and tropospheric conditions, satellite geometry, baseline length, multipath effects and the presence of intentional or unintentional interference. 2. Model-configurable to track L5/E5a (all / Galileo) through L2 (GPS) or L3/E5b/B2 (GLONASS / Galileo / BeiDou) through L2 (GLONASS). See manual for details. 3. Hardware ready for L3 and L5. 4. E1bc and E6bc support only. 5. L-Band and SBAS reception on primary antenna only. 6. GPS-only. 7. Requires a subscription to a TerraStar data service. Subscriptions available from NovAtel. 8. Typical value. No almanac or ephemerides and no approximate position or time. 9. Typical value. Almanac and recent ephemerides saved and approximate position and time entered. 10. Time accuracy does not include biases due to RF or antenna delay. 11. Export licensing restricts operation to a maximum of 515 meters per second, message output impacted above 500 m/s. 12. Supplied by IMU manufacturer. 13. Typical values using serial port communication without interference mitigation. Consult the OEM7 User Documentation for power supply considerations. 14. GNSS only. IMU measurements may not be valid. 15. 1ppm should be added to all position values to account for additional error due to baseline length. 16. Post-processing results using Inertial Explorer software. The survey data used to generate these statistics had frequent changes in azimuth.



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