



Accurate
positioning

22°39'48.37"N 114°02'10.91"E



JS-MK39-F

PRODUCT SPECIFICATION

Data Sheet



Shenzhen Jumpstar Technology Co.,Ltd

Email : info@jumpstar-tech.com

Tel : (86) 0755-23732282

Fax : (86) 0755-23732823

Add : Room 213, Building B, Youth Pioneer Park, Jianshe East Road,
Longhua District, Shenzhen, Guangdong Province, China, 518109.

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Change History of Revision

Revision	Date	Contents of Revision Change	Remark
V1.0	2019-01-18	First release	Li pengfei
V1.1	2021-12-16	Added temperature description for farad capacitors & Incgram	Wang Wei
V1.2	2022-01-08	Software upgrade	Wang Wei
V1.3	2022-04-09	PIN definition changes and hardware upgrades	Wang Wei

1 Functional description

1.1 Overview

The MK39-F are concurrent GNSS receivers that can receive and track multiple GNSS systems. Owing to the multi-band RF front-end architecture. Can support BDS B1 B2, GPS L1 L2, GLONASS G1 G2 three system 6 frequency points at the same time. All satellites in view can be processed to provide an RTK navigation solution when used with correction data. The MK39-F receiver can be configured for concurrent GPS, GLONASS, BDS plus QZSS reception, to provide a high performance position reporting and navigation solution. Based on the high performance MK39-F position engine, these receivers provide exceptional sensitivity and acquisition times and interference suppression measures enable reliable positioning even in difficult signal conditions.

1.2 Product features

- Build on high performance GNSS SOC
- 96 search channels and 60 trace channels
- Cold start acquisition sensitivity of -147dBm and -163dBm tracking sensitivity
- Default 1Hz navigation update rate
- Supports GPS,BDS, GLONASS, QZSS
- Support the Beidou-3 satellite
- Integrated TCXO,LNA,SAW,RTC
- Configurable peripheral IO pins
- It is characterized by high sensitivity, anti-interference and high performance
- Low power consumption and it has intelligent power control mechanism
- Single supply with wide voltage range
- Compact size (25.0*39.4*11.6mm±0.3mm) suitable for space-sensitive application
- Support NMEA 0183(compatible with Beidou) 、 RTCM3. X and user-defined

1.3 Performance

Parameter	Specification	
Receiver type	■GPS L1C/A L2C ■GLONASS G2 G1 ■BDS B1I B2I	
Sensitivity	Tracking	-163dBm
	Reacquisition	-147dBm
Time-To-First-Fix ¹	Cold Start	≤35 s
	Hot Start	1s
Position accuracy ²	Autonomous	2.0 m
	DGNSS	0.5m
	RTK	2cm+1ppm (Horizontal) ³
Accuracy of time pulse signal	RMS	30ns
Velocity accuracy ⁴	0.05 m/s	
Operational limits ⁵	Dynamics	≤ 4 g
	Altitude	≤ 18000 m
	Velocity	≤ 515 m/s
Baud Rate	115200-230400bps (Default 115200 bps)	
Max navigation update rate	10 Hz (Default 1Hz)	

✎₁ All satellites at ≥-130dBm

✎₂ CEP 50%, 24 hours static, ≥-130dBm, > 6SVs

✎₃ Based on 30km, the accuracy error increases by 1cm every 10km from the base station

✎₄ 50% @30m/s

✎₅ Assuming airborne <4g(Dynamics) platform

1.4 Supported GNSS constellations

The MK39-F GNSS modules are concurrent GNSS receivers that can receive and track multiple GNSS systems. Owing to the multi-band RF front-end architecture, all four major GNSS constellations (GPS, GLONASS and BDS) can be received concurrently. All satellites in view can be processed to provide an RTK navigation solution when used with correction data. The MK39-F receiver can be configured for concurrent GPS, GLONASS and BDS plus QZSS reception. If power consumption is a key factor, then the receiver can be configured for a sub-set of GNSS constellations.

The QZSS system shares the same L1 and L2 frequency bands as GPS and can always be processed in conjunction with GPS.

The MK39-F supports the GNSS and their signals as shown in Table

GPS	GLONASS	BDS
L1C/A (1575.42 MHz)	L1OF ($1602 \text{ MHz} + k \cdot 562.5 \text{ kHz}$, $k = -7, \dots, 5, 6$)	B1I (1561.098 MHz)
L2C (1227.60 MHz)	L2OF ($1246 \text{ MHz} + k \cdot 437.5 \text{ kHz}$, $k = -7, \dots, 5, 6$)	B2I (1207.140 MHz)

Table : Supported GNSS and signals on MK39-F

⚠ BDS B2I is not enabled by default.

1.5 RTK operation

1.5.1 Rover navigation modes

In its default configuration the MK39-F Rover will attempt to provide the best positioning accuracy dependant on the received correction data. It will enter RTK Float mode as soon as it receives an input stream of RTCM messages. Once the Rover has resolved the carrier phase ambiguities it will enter RTK Fixed mode. It is when the Rover is in RTK Fixed mode that the relative accuracies can be expected to be correct to the cm-level.

The reference frame of the reference receiver (or base) must be transformed by the user into the required system being used by their application and mapping system. If comparing the rover position with a reference system the same RTCM stream should be used to ensure the reference and rover are outputting the same position. If doing post processing of a reference system its output must be transformed to same ITRF and datum being used by the rover.

RTK is a differential system where the rover uses the reference datum of the reference station. The International Terrestrial Reference Frame (ITRF) must be obtained from the reference network and then used to transform the rover position output to match the required reference frame. The rover will not output the

position in the local receiver WGS84 (based on ITRF2008) datum, it will match the reference receiver (or base) reference frame. The user application will need to do the transformation for use in a mapping application if it does not use the same reference frame. An offset can occur if this is not done.

If RTCM corrections become unavailable, the rover will run as a standalone precision receiver.

The command of UBX-CFG-DGNSS can be used to specify that the receiver should stay in RTK Float mode and that it should not attempt to fix integer ambiguities.

The current operation mode is indicated by relevant NMEA and UBX-NAV messages.

1.5.2 Base station mode

The RTK rover needs RTCM corrections in order to achieve high precision results. These corrections come from a local receiver (the base), or via a reference receiver. If the two receivers are local to each other they are called the base and rover. If the rover is provided its corrections from a system such as VRS/CORS it is provided its corrections from a service or reference receiver.

The corrections can be supplied to the MK39-F using several interfaces: UART

The link between the rover and the source of the corrections can be any form of wireless link: Cellular, WIFI, Bluetooth, proprietary radio, ISM etc. The user only needs to ensure the RTCM messages arrive at the I/O port selected on the MK39-F. This link will be bi-directional for a VRS services as the rover has to provide its position usually every 30 seconds at least.

Instead of using two local receivers in a base and rover configuration you can use a correction service that can be accessed over the internet. The rover receives corrections in RTCM format that are provided over the internet via a NTRIP service. This requires that an NTRIP client processes the corrections from an NTRIP server on the internet. This client will be implemented on a host application connected to the rover. There are many open source variants of NTRIP clients available that can be implemented on embedded or Windows, Linux, Android systems.

The configuration of the RTCM 3x correction stream must be done according to the following rules:

- All observation messages must be broadcast at the same rate.
- The reference station ID field in the GPS, GLONASS, BDS observation messages must be consistent with the reference station ID field in the reference station message otherwise the rover will not be able to compute its position.
- The RTCM 3x stream must contain the "GLONASS code-phase biases" message (type 1230) or the "

Receiver and Antenna Description" message (type 1033) otherwise the GLONASS ambiguities can only be estimated as float, even in RTK fixed mode. If using a MK39-F as a base, "GLONASS code-phase biases" message (type 1230) must be enabled to be output. For a MK39-F being used as a rover if no RTCM 1230 message is received, or if the reference receiver type reported in RTCM 1033 message is unknown to the MK39-F receiver, the MK39-F rover will only be able to estimate GLONASS ambiguities as float, even in RTK fixed mode. This will result in degraded performance, especially in challenging environments.

- The static reference station message (type 1005 or type 1006) does not need to be broadcast at the same rate as the observation messages however the rover will not be able to compute its position until it has received a valid reference station message.
 - The RTCM 3x stream should only contain one type of observation messages per constellation. When using a multi-constellation configuration, all constellations should use the same type of observation messages. Mixing RTK and MSM messages will result in undefined rover behavior.
 - If the receiver is configured to output RTCM messages on several ports, they must all have the same RTCM configuration otherwise the MSM multiple message bit might not be set properly.
- ☞ If you want to use base station mode, please contact us.

1.6 Product Application

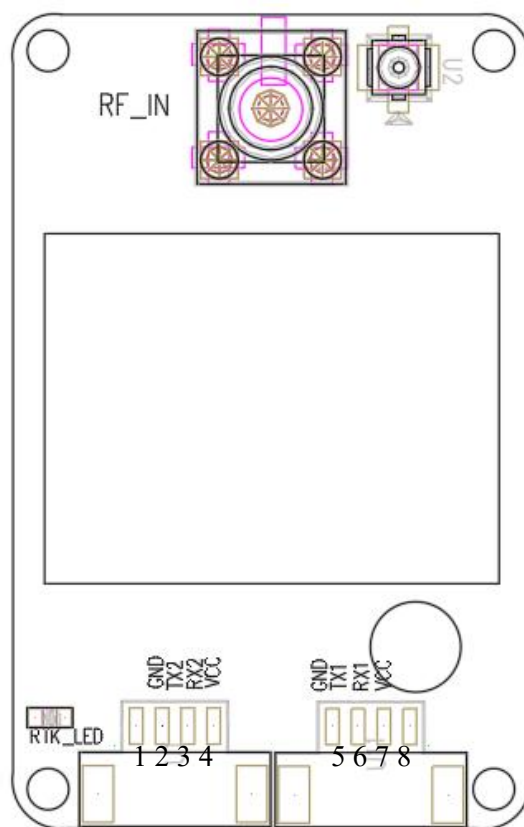
- UAV
- Automotive application
- Precision agriculture
- AVL and Location-Based Services
- Marine Navigation, Fleet Management
- Handheld GPS receiver application
- Intelligent logistics scheduling
- Measurement of surveying and mapping
- Personnel protective
- Driving test
- Ideal for PDA
- Car navigation and tracking
- Geographic Surveying
- Intelligent robot

Protocol	Type
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NMEA 0183 V4.0/4.1	Input/output, ASCII
RTCM 3X	Input/output, binary
JMS	Custom

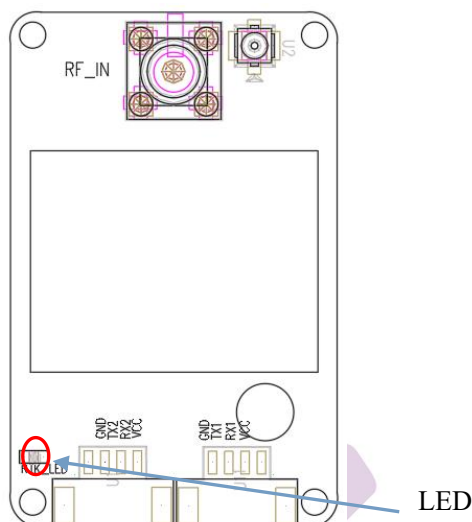
2 Pin definition

2.1 Pin assignment



No.	Name	I/O	Description
1	GND	G	Ground
2	TX2	O	NC
3	RX2	I	Serial Port (dedicated for RTCM3 corrections and NMEA.)
4	VCC	P	Main Supply
5	GND	G	Ground
6	TX1	O	GPS TX Test
7	RX1	I	GPS RX Test
8	VCC	P	Main Supply

2.2 LED Indicator Status



LED Indicator	In working condition
Normally on	FIXED
Twinkle	Once in three seconds (3D) ; A half-second flicker (Receiving RTCM data) ; Flicker once a second (Float)
Extinguish	Unlocated state

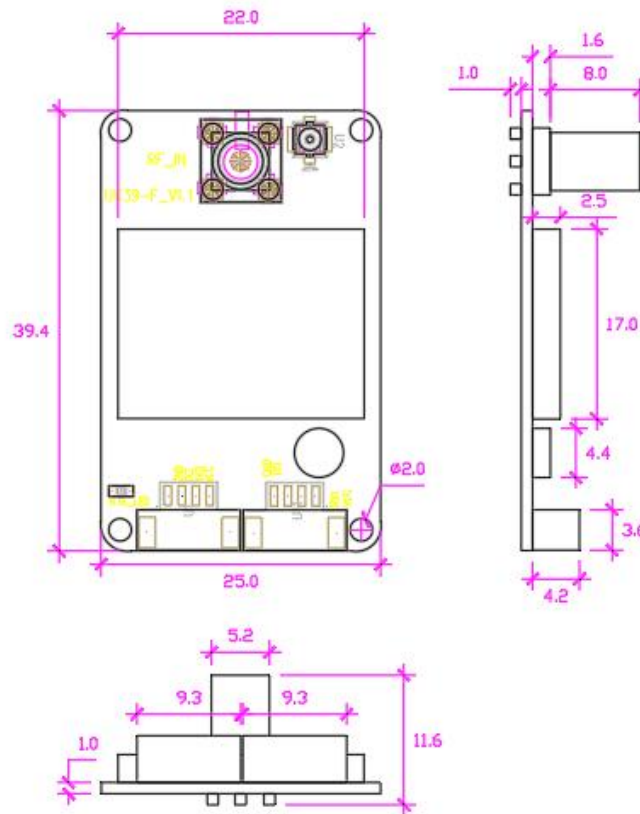
3 Electrical specifications

Parameter	Symbol	Min	Typ	Max	Units
Power supply voltage	VCC	3.3	5.0	5.5	V
Average supply current	Acquisition	90@5.0V	110@5.0V	130@5.0V	mA
	Tracking	90@5.0V	95@5.0V	120@5.0V	mA
Backup battery			0.07		F
Digital IO voltage	Div	3.3		5.5	V
Storage temperature	Tstg	-45		85	°C
Operating temperature ¹	Topr	-40		85	°C
Farah capacitance ²	Tstg	-25		60	°C
Humidity				95	%

¹ The temperature range is the operating temperature range without the Farad capacitor

² Hot start cannot be carried out when the temperature is below -20°C or above 60°C

4 Mechanical specifica



Unit: mm Error: $\pm 0.3\text{mm}$

5 Interface configuration selection

5.1 Interfaces description

The MK39-F module include one UART interface, which can be used for communication to a host. You can choose any one of the output interface output data, It supports configurable baud rates.

5.2 Interface configuration selection

The MK39-F series GNSS module can be selected based on the corresponding interface output. There are mainly the following options. The relevant sensor is an optional part that can be selected according to actual needs.

NAME	TTL	RS232	USB	QMC5883L
MK39-F	√	--	--	--

6 UART interface

There are two UART interfaces: UART1 and UART2. UART1 is the primary host communications interface while UART2 is dedicated for RTCM3 corrections and NMEA. No UBX protocol is supported. UART1 and UART2 operate up to and including a speed of 921600 baud. No hardware flow control on UART1 and UART2 is supported.

UART1 is enabled by default if D_SEL = 1 or open.

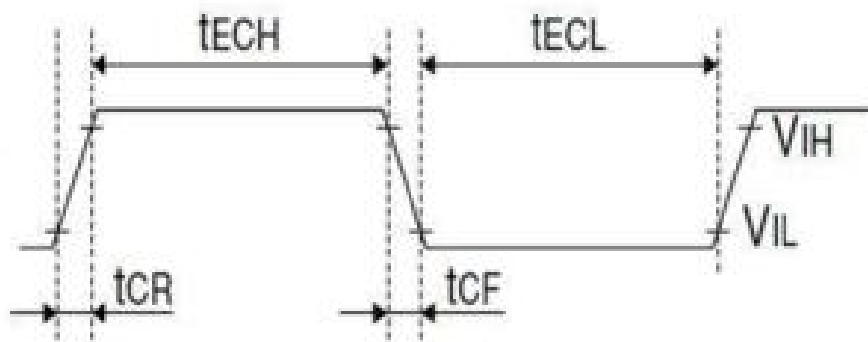
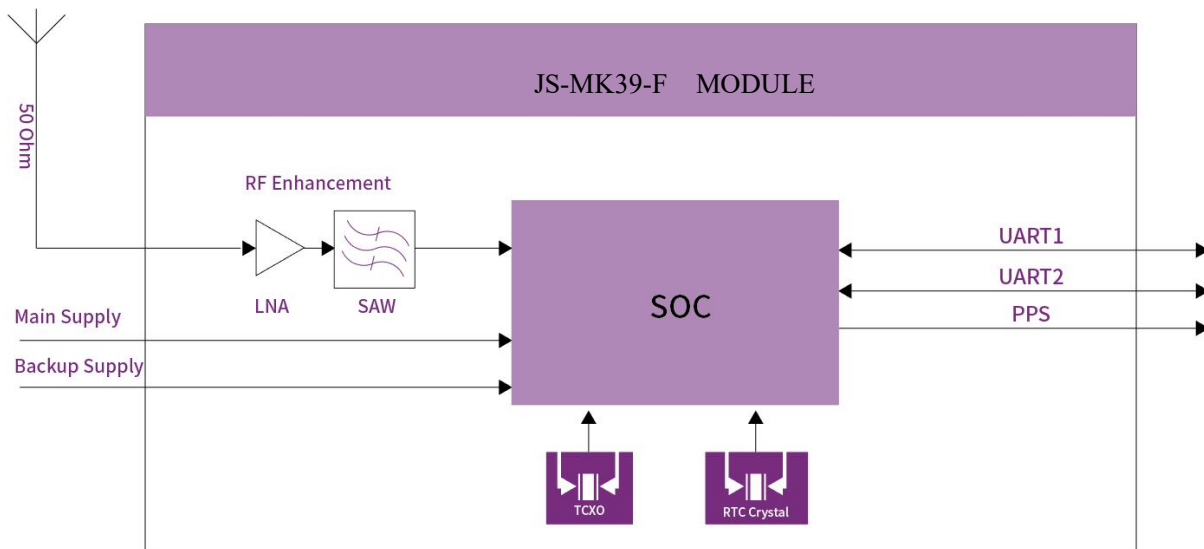


Figure: MK39-F high precision receiver UART timing specifications

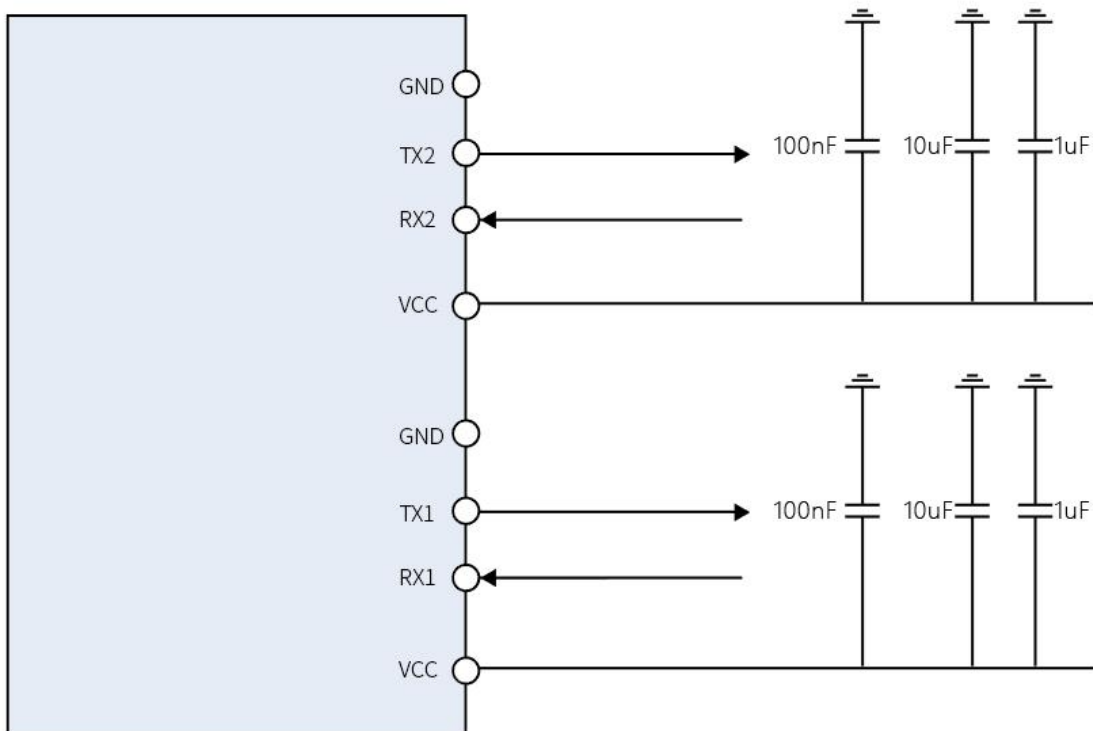
Symbol	Symbol	Min	Max	Units
VIL	LOW-level input voltage	0	0.2VCC	V
VIH	HIGH-level input voltage	0.7VCC	VCC+0.3	mA
tECH	HIGH period of External data input	0	0.4	μs
tECL	Low period of External data input			μs
Ru	Baudrate	9600	921600	bps
tCR	Rise time of Data	-40	5	ns
tCF	Fall time of Data	-40	5	ns

Table:MK39-F UART timings and specifications

6.1 Block Diagram



6.2 Application Circuit



7 ROHS

7.1 RoHS Compliance

This product is RoHS compliance