

Introduction to GAMIT/GLOBK

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Preface

GAMIT/GLOBK is a comprehensive GNSS analysis package developed at MIT, the Harvard-Smithsonian Center for Astrophysics (CfA), Scripps Institution of Oceanography (SIO), and Australian National University for estimating station coordinates and velocities, stochastic or functional representations of post-seismic deformation, atmospheric delays, satellite orbits, and Earth orientation parameters. Although the software is currently maintained by the three authors of this document at MIT, many people have made substantial contributions. The orbital integration and modules used in computing the theoretical phase observable have their origins in the Planetary Ephemeris Program (PEP) written by Michael Ash, Irwin Shapiro, and Bill Smith at Lincoln Laboratory in the 1960's, with later contributions by Bob Reasenberg and John Chandler at MIT. The codes for processing GPS observations were developed at MIT in the 1980's by Chuck Counselman, Sergei Gourevitch, Yehuda Bock, Rick Abbot, and King. GAMIT attained its current form through the efforts of Bock, Danan Dong, Peng Fang (SIO), Kurt Feigl, Herring, King, McClusky (ANU), Mike Moore (ANU), Peter Morgan (Canberra U), Mark Murray (NM Tech), Liz Petrie (U Newcastle), Berkhard Schraffin (Ohio State), Seiichi Shimada (NEID), Paul Tregoning (ANU), and Chris Watson (U Hobart). GLOBK was developed by Herring and Jim Davis at CfA for combination of VLBI data and modified at MIT to incorporate GPS data. Details of these contributions may be found in the references listed at the end of this manual. Funding for the early development of GAMIT was provided by the Air Force Geophysics Laboratory, and for GLOBK by NASA. Current support for development and support of the scientific community comes primarily from the National Science Foundation.

To control processing the software uses C-shell scripts (stored in /com and mostly named to begin with *sh_*) which invoke the Fortran or C programs compiled in the /libraries, /gamit, and /kf directories. The software is designed to run under any UNIX operating system supporting X-Windows, including LINUX and MacOS. The parameter logic allows a maximum of 99 sites and the standard distribution is dimensioned for 80 sites, but since the run is proportional to the cube of the number of parameters, with networks larger than 50 sites greater efficiency is obtained by parallel processing using connected subnets. IGS processing at MIT includes over 300 sites, and processing at New Mexico Tech for the North American Plate Boundary Observatory over 1000 sites.

The first chapter of this manual provides some theoretical background for readers not familiar with high-precision GNSS analysis. Chapter 2 describes the setup of tables and commands for automatic processing to obtain time series of daily position estimates, and Chapter 3 provides a guide to evaluating your results. In Chapter 4 we discuss various approaches to generating time series and estimating station velocities from observations spanning several years. More detailed documentation is available in the longer *GAMIT Reference Manual* and *GLOBK Reference Manual*. There are also tutorials available on-line at <http://www-gpsg.mit.edu>. The most up-to-date information about the commands is available through help files, invoked by typing the name of the shell-script or program without arguments.

1. GNSS Measurements and Analysis

1.1 Phase and pseudorange observations

High-precision geodetic measurements with GNSS are performed using the carrier beat phase, the output from a single phase-tracking channel of a GNSS receiver. This observable is the difference between the phase of the carrier wave implicit in the signal received from the satellite, and the phase of a local oscillator within the receiver. The phase can be measured with sufficient precision that the instrumental resolution is a millimeter or less in equivalent path length. The dominant source of error in a phase measurement or series of measurements between a single satellite and ground station is the unpredictable behavior of the time and frequency standards ("clocks") serving as reference for the transmitter and receiver. Even though the satellites carry atomic frequency standards, the instability of these standards would still limit positioning to the several meter level were it not for the possibility of eliminating their effect through signal differencing.

A second type of GNSS measurement is the pseudo-range, obtained using the codes transmitted by the satellites. Pseudo-ranges provide the primary GNSS observation for navigation but are not precise enough to be used directly in geodetic surveys. They are useful, however, for estimating the offsets of receiver clocks, resolving ambiguities, and repairing cycle slips in phase observations.

For a single satellite, differencing the phases (or pseudo-ranges) of signals received simultaneously at each of two ground stations eliminates the effect of bias and instabilities in the satellite clock. This measurement is commonly called the between-stations-difference, or single-difference observable. Forming a second difference, between satellites, eliminates the effect of bias and instabilities in the station blocks.

Since the phase biases of the satellite and receiver oscillators at the initial epoch are eliminated in doubly differenced observations, the doubly differenced range (in phase units) is the measured phase plus an *integer* number of cycles. (One cycle has a wavelength of 19 cm at GPS L1 and 24 cm at GPS L2 for code-correlating receivers; half these values for squaring-type receivers used prior to the mid-1990s, and slightly different values for the primary frequencies transmitted by Glonass, Beidou, and Galileo. In the manuals we will use the term "L1" to refer to the higher and "L2 the lower of the two L-band frequencies though these may be, e.g. for Galileo E1(L1) and E5.) If the measurement errors, arising from errors in the models for the orbits and propagation medium as well as receiver noise, are small compared to a cycle, there is the possibility of determining the integer values of the biases, thereby obtaining from the initially ambiguous doubly differenced phase an unambiguous measure of doubly differenced range. Resolution of the phase ambiguities improves the uncertainties in relative position measures by about a factor of 1.5 for 24-hr sessions, 3 for 8-hr sessions and more than 5 for short sessions. (see, e.g., *Blewitt [1989]*, *Dong and Bock [1989]*).

GAMIT incorporates difference-operator algorithms that map the carrier beat phases into singly and doubly differenced phases. These algorithms extract the maximum relative positioning information from the phase data regardless of the number of data outages, and take into account the correlations that are introduced in the differencing process. (See *Bock et al.* [1986] and *Schaffrin and Bock*[1988] for a detailed discussion of these algorithms.) An alternative, (nearly) mathematically equivalent approach to processing GNSS phase data is to use formally the (one-way) carrier beat phases but estimate at each epoch the phase offset due to the station and satellite clocks. This approach is used by the *autcln* program in GAMIT to compute one-way phase residuals for editing, display, and estimating atmospheric and ionospheric slant delays.

In order to provide the maximum sensitivity to geometric parameters, the carrier phase must be tracked continuously throughout an observing session. If there is an interruption of the signal, causing a loss of lock in the receiver, the phase will exhibit a discontinuity of an integer number of cycles (“cycle-slip”). This discontinuity may be only a few cycles due to a low signal-to-noise ratio, or it may be thousands of cycles, as can occur when the satellite is obstructed at the receiver site. Initial processing of phase data is often performed using time differences of doubly differenced phase ("triple differences", or "Doppler" observations) in order to obtain a preliminary estimate of station or orbital parameters in the presence of cycle slips. The GAMIT software uses triple differences in editing but not in parameter estimation. Rather, it allows estimation of extra bias parameters whenever the automatic editor has flagged an epoch as a cycle slip that cannot be repaired. Various algorithms to detect and repair cycle slips are described by *Blewitt* [1990], and also in Chapter 4 of the *GAMIT Reference Manual*.

Although phase variations of the satellite and receiver oscillators effectively cancel in doubly differenced observations, errors in the *time* of the observations, as recorded by the receiver clocks, do not. However, the pseudo-range measurements, together with reasonable a priori knowledge of the station coordinates and satellite position, can be used to determine the offset of the station clock to within a microsecond, adequate to keep errors in the doubly differenced phase observations below 1 mm.

A major source of error in single-frequency GNSS measurements is the variable delay introduced by the ionosphere. For day-time observations near solar maximum this effect can exceed several parts per million of the baseline length. Fortunately, the ionospheric delay is dispersive and can usually be reduced to a millimeter or less by forming a particular linear combination (LC) of the L1 and L2 phase measurements:

$$\phi_{LC} = 2.546 \phi_{L1} - 1.984 \phi_{L2} \quad (1)$$

for GPS (see, e.g., *Bock et al.* [1986], or *Dong and Bock* [1989].) Forming LC, however, magnifies the effect of other error sources. For baselines less than a few kilometers the ionospheric errors largely cancel, and it is preferable to treat L1 and L2 as two independent observables rather than form the linear combination. The station separation at which the ionospheric errors exceed the phase noise depends on many

factors (receiver, antenna, multipath environment, latitude, time of day, sunspot activity) and must be determined empirically by analyzing the data with both observable types.

In examining phase data for cycle slips, it is often useful to plot several combinations of the L1 and L2 residuals. Single-cycle slips in GPS L1 or L2 will appear as jumps of 2.546 or 1.984 cycles, respectively, in LC. Single-cycle slips in both GPS L1 and L2 (a more common occurrence) appear as jumps of 0.562 cycles in LC, which, though smaller, may be more evident than the jumps in L1 and L2 because the ionosphere has been eliminated. If the L2 phase is tracked using codeless techniques, the carrier signal recorded by the receiver is at twice the L2 frequency, leading to half-cycle jumps when it is combined with full-wavelength data. Hence, a jump of a "single" L2 cycle will appear as 0.992 in LC, and simultaneous jumps in (undoubled) L1 and (doubled) L2 will appear as 1.554 cycles in LC. Another useful combination is the difference between L2 and L1 with both expressed in distance units

$$\phi_{LG} = \phi_{L2} - 0.779 \phi_{L1} \quad (2)$$

for GPS, called "LG" because the L2 phase is scaled by the "gear" ratio ($f_2/f_1 = 60/77 = 1227.6/1575.42$ for GPS). In the LG phase all geometrical and other non-dispersive delays (e.g., the troposphere) cancel, so that we have a direct measure of the ionospheric variations. One-cycle slips in L1 and L2 are difficult to detect in the LG phase in the presence of much ionospheric noise since they are equivalent for GPS to only 0.221 LG cycles.

If precise (P-code) pseudorange is available for both GNSS frequencies, then a "wide-lane" (WL) combination of L1, L2, P1, and P2 can be formed which is free of both ionospheric and geometric effects and is simply the difference in the integer ambiguities for L1 and L2:

$$WL = n_2 - n_1 = \phi_{L2} - \phi_{L1} + (P1 + P2) (f_1 - f_2)/(f_1 + f_2) \quad (3)$$

The WL observable can be used to fix cycle slips in one-way data [Blewitt, 1990] but should be combined with LG and doubly differenced LC to rule out slips of an equal number of cycles at L1 and L2.

These various combinations of phase and pseudorange observations are used not only in data editing, but also in resolving the phase ambiguities. When the LC observable is used, we determine the L1 and L2 ambiguities by first resolving $n_2 - n_1$ ("widelane") and then n_1 ("narrow lane"). If precise and unbiased pseudoranges are available, the widelane ambiguities can be resolved for baselines up to thousands of kilometers under any ionosphere conditions. For measurements prior to 1995, and possibly prior to 2000, inter-channel receiver biases can corrupt the pseudoranges and it is necessary to use the phase observations alone with a constraint on the ionosphere to resolve the widelane ambiguities (see, e.g., Blewitt, 1989; Dong and Bock, 1989; Feigl et al., 1993). GAMIT gives you the option of selecting the method to be used, either pseudoranges (LC_AUTCLN) or ionospheric constraints (LC_HELP). When using the pseudorange approach with

different receiver types, it is important to use the satellite-dependent differential code biases (DCBs) computed from tracking data by the Center for Orbit Determination in Europe (CODE) [<http://www.aiub.unibe.ch/ionosphere.html>] and updated monthly at MIT in file dcb.dat. Once the wide-lane ambiguity for a given doubly differenced combination has been resolved, resolving the narrow-lane ambiguity for that combination depends on the level of noise from the receiver, multipathing, and the troposphere, and the accuracy of the models employed for the position and motion of the stations and satellites. It is generally more difficult to resolve these ambiguities for the longest baselines, but for data acquired since 2000 we can usually resolve 80-95% of the ambiguities in a global analysis.

Although GAMIT can process data from single-frequency receivers, ionospheric errors begin to limit relative positioning accuracy for station separations greater than 100-2000 m, depending on time of day, latitude, and the solar sunspot cycle. So for most applications, the use of two frequencies is required to remove first-order ionospheric effects. Although some GNSS satellites transmit signals on three or more frequencies, GAMIT is currently limited to using only two. GAMIT is also limited to processing data from only one GNSS at a time, though the GAMIT position estimates from several GNSS tracked during a session can easily be combined in GLOBK.

1.2 Modeling the motions of the satellites and stations

A first requirement of any GNSS geodetic experiment is an accurate model of the satellites' motion. The (3-dimensional) accuracy of the estimated baseline, as a fraction of its length, is roughly equal to the fractional accuracy of the orbital ephemerides used in the analysis. The accuracy of the navigation (“broadcast”) orbit computed by the GNSS control centers using pseudorange measurements from < 15 tracking stations is typically 1-5 parts in 10^7 (2-10 m), well within the navigation design specifications for the system but not accurate enough for the study of crustal deformation. By using phase measurements from a global network of over 100 stations, however, the International GNSS Service (IGS) [Beutler *et al.*, 1994a], is able to determine the satellites' motion with an accuracy of 1 part in 10^9 (2 cm; 5-20 cm in earlier years; see <http://acc.igs.org>) For GPS surveys prior to 1994, the global tracking network was much smaller but can still be used to achieve accurate results for regional surveys. If we estimate orbital parameters and include in our analysis observations from widely separated stations whose coordinates are well known, the fractional accuracy of the baselines formed by these stations is transferred through the orbits to the baselines of a regional network. For example, a 10 mm uncertainty in the relative position of sites 2500 km apart introduces an uncertainty of only ~1 mm in the components of a 250 km baseline. This scheme can be used successfully even with regional fiducial stations, transferring, for example, the relative accuracy of 250-500 km baselines to a network less than 100 km in extent, a helpful approach with surveys conducted prior to the availability of precise global orbits.

The motion of a satellite can be described, in general, by a set of six initial conditions (Cartesian position and velocity, or osculating Keplerian elements, for example) and a model for the forces acting on the satellite over the span of its trajectory. To model

accurately the motion, we require knowledge of the acceleration induced by the gravitational attraction of the Sun, Moon, higher order terms in the Earth's static gravity field, solid-Earth and ocean tides, and some means to account for the action of non-gravitational forces due to direct solar radiation pressure, radiation reflected from the Earth, radiation emitted by the spacecraft's radio transmission, and gas emission by the spacecraft's batteries and attitude-control system. For all GNSS satellites non-gravitational forces are the most difficult to model and have been the source of considerable research over the past 20 years (see *Colombo* [1986], *Beutler et al.* [1994b], and *Ziebart et al.* [2002] for more discussion).

In principle, a trajectory can be generated either by analytical expressions or by numerical integration of the equations of motion; in practice, numerical integration is almost always used, for both accuracy and convenience. The position of the satellite as a function of time is then read from a table (ephemeris) generated by the numerical integration. In GAMIT the integration is performed by program *arc* using equations given by *Ash* [1972].

Besides the orbital motion of a satellite, we must take into account meter-level offsets between its center of mass and the phase-center of the transmitting antenna, including temporary excursions of several decimeters lasting up to a half-hour during the maneuvers the satellites execute to keep their solar panels facing the Sun when the orbital plane is nearly aligned with the Earth-Sun direction. For the satellites in each orbital plane, this alignment occurs for several weeks twice a year, the so-called "eclipse season". Yoaz Bar-Sever and colleagues at JPL have spent considerable effort developing models of the satellites' orientation, even to point of making the behavior more predictable by getting the US Defense Department to apply a small bias about the yaw axis to GPS satellites—a change that was implemented gradually between June, 1994, and November, 1995. See *Bar-Sever* [1996] and *Kouba* [2009] for a discussion of GPS yaw, and *Montenbruck et al.* (2015) for other GNSS.

The position of the ground station in the Earth-centered inertial system defined by the satellites' orbits is affected by a number of geophysical phenomena. These include the Earth's rotation, precession and nutation of the spin axis in inertial space, motion of the spin axis with respect to the crust ("wobble"), luni-solar solid-body tides, and loading of the crust by ocean tides and the atmosphere. All of these effects are incorporated into the model of the phase and pseudorange observations computed in program *model*.

In modeling the phase and pseudorange observations, we must also take into account changes in the apparent distance due to variations in the phase centers of the transmitting and receiving antennas. With matched ground antennas in a regional network, these effects nearly cancel, but for longer baselines and/or different antenna types they can amount to several centimeters in estimated heights. Models for the phase center offsets (PCOs) and variations (PCVs) with elevation and azimuth for most commonly used ground antennas have been determined by electro-mechanical measurements [<http://gnpcvdb.geopp.de>; <http://www.ngs.noaa.gov/ANTCAL>], and for the satellite antennas by analysis of global tracking data [*Schmid et al.*, 2007].

Also part of the phase and pseudorange model is the propagation delay caused by the neutral part of the Earth's atmosphere. This effect is represented by a time-dependent "zenith delay", a "mapping function" that extends the delay to other elevation angles, and a simple function for north-south and east-west gradients. The zenith hydrostatic ("dry") delay (ZHD) can be well represented by surface pressure, available either from an empirical function of latitude, longitude, and season (the GPT2 model of *Legler et al.*, 2013) or at six-hour intervals from a numerical weather model as computed by TU Vienna (VMF1) (*Boehm et al.*, 2006) and distributed in yearly grid files by MIT for GAMIT users. The hydrostatic and "wet" mapping functions are also part of both the GPT2 and VMF1 models. The component of the zenith delay due to water vapor (zenith "wet" delay, ZWD) and the local gradients cannot be accurately determined even from a numerical weather model and must be estimated from the GPS data. The details of these models are described in Chapter 7 of the *GAMIT Reference Manual*. As noted above the first-order effect of the ionosphere on the signal delay is made nearly negligible by combining L1 and L2 measurements. However, during periods of high ionospheric activity, 2nd and 3rd order effects at the millimeter to centimeter level are possible and can be modeled in GAMIT using the approach described by *Petrie et al.* [2010].

1.3 Parameter estimation

GAMIT (program *solve*) incorporates a weighted least squares algorithm to estimate the relative positions of a set of stations, orbital and Earth-rotation parameters, zenith delays, and phase ambiguities by fitting to doubly differenced phase observations. Since the functional (mathematical) model relating the observations and parameters is non-linear, GAMIT produces two solutions, the first to obtain coordinates within a few decimeters, and the second to obtain the final estimates. (See the discussion in Section 2.2 of the *GAMIT Reference Manual*.)

In current practice, the GAMIT solution is not usually used directly to obtain the final estimates of station positions from a survey. Rather, we use GAMIT to produce estimates and an associated covariance matrix ("quasi-observations") of station positions and (optionally) orbital and Earth-rotation parameters which are then input to GLOBK or other similar programs to combine the data with those from other networks and times to estimate positions and velocities [*Feigl et al.*, 1993; *Dong et al.*, 1998]. GLOBK uses a Kalman filter (equivalent to sequential least squares if there are no stochastic parameters in the solution) which operates on covariance matrices rather than normal equations and hence requires that you specify a non-infinite a priori constraint for each parameter estimated (see, e.g., *Herring et al.* [1990]). In order not to bias the combination, GAMIT generates the solution used by GLOBK with loose constraints on the parameters. Since phase ambiguities must be resolved (if possible) in the phase processing, however, GAMIT also generates several intermediate solutions with user-defined constraints before loosening the constraints for its final solution. These steps are described in detail in Section 3.4 of the *GAMIT Reference Manual*.

In parameter estimation based on least-squares, the conventional measure of goodness-of-fit is the χ^2 (chi-square) statistic, defined for uncorrelated data as the sum of the squares of each observation residual (post-fit observed minus computed observation, “o-c”) divided by its assigned uncertainty. In a GPS analysis parameter correlations arise (even if not represented in the original data weights) so the computation of χ^2 in GAMIT or GLOBK involves a complex matrix operation (see *Dong et al.*, [1998]), but the idea is the same. The value of χ^2 is usually normalized by dividing by the “degrees of freedom” (*df*), the number of observations minus the number of parameters estimated, so that the ideal value for properly weighted, independent random observations is 1.0. Conversely, with whatever a priori weight is assigned to the observations, multiplying the estimated parameter uncertainties by the square root of χ^2/df yields the “formal errors” (“formal standard deviations”) of the parameter. With white noise, these formal uncertainties will be realistic and will be inversely proportional to the square root of the number of observations (i.e., will depend strongly on the sampling interval).

The uncertainties in a GNSS analysis, however, cannot be treated with white noise statistics because errors with temporal correlations dominate both the phase observations and estimates of station coordinates (the quasi-observations input to GLOBK). In the phase residuals (from *cview* or the sky plots produced by *sh_gamit*), the visible noise—from multipathing and tropospheric fluctuations—is typically correlated over spans of 15-30 minutes. This implies that only samples taken at these intervals are independent, and, to a first approximation, we would get realistic uncertainties by multiplying the formal errors by the square root of the ratio of this interval to the sampling interval used—e.g., for the 2 minute sampling commonly used in *solve*, we would increase the uncertainties by a factor of 3-5. There also errors with longer correlation times that do not show up in the residuals but are absorbed into the parameter adjustments. Assessing the magnitude of these errors requires us to use noise visible in the residuals (phase or coordinates) to infer the character of the noise at lower frequencies. There are a number of excellent studies of the character of the errors discussed in the presentation ‘Error_Analysis.ppt’ from our most recent workshops on the Documentation page of the GAMIT/GLOBK web site (e.g., *Mao et al.* [1999], *Dixon et al.* [2000], and *Williams* [2003]). Once you have adopted a particular weighting of the data, it is often possible to use external knowledge of the expected behavior of the coordinates or velocities to validate the uncertainties; see *McClusky et al.* [2000], *Davis et al.* [2003], and *McCaffrey et al.* [2007].

In GAMIT/GLOBK there are several ways you can control the uncertainties you obtain for coordinates and velocities, and it is important for you to keep clearly in mind how each of these operates. The uncertainties generated by *solve* and passed to GLOBK in the h-file are determined by the a priori error assigned to the phase observations and by the sampling interval—*solve* does not rescale by the square root of χ^2/df (“postfit nrms” in the q-file). In the initial (“preliminary”) solution, we normally assign an uncertainty of 10 mm to each one-way L1 phase. By Equation (1), the assigned uncertainty in an LC phase becomes 32 mm. The mean rms of one-way LC residuals is typically ~6-9 mm, so the nrms computed by *solve* is 0.2-0.3. In the second (“final”) solution, we normally reweight the observations using a constant and elevation-dependent term computed in

data editing by program *autcln* from the actual (one-way LC) phase residuals. In order to keep the overall weighting approximately the same as with the 10 mm constant error, the values computed by *autcln* (ATELV table in file *autcln.post.sum*) are multiplied by an arbitrary factor of 1.7 (in script *sh_sigelv*) before being input to *solve* (via the N-file). We chose to use inflated values of the a priori phase error and not rescale by the nrms in order to generate coordinate uncertainties that (in the presence of correlated noise) are approximately realistic with 2-minute sampling. An equally valid approach would be to rescale by the nrms (i.e. make $\chi^2/df=1.0$) and compensate later for the unrealistically low coordinate uncertainties. With whatever weighting you use in *solve*, you can increase the coordinate uncertainties used by GLOBK by rescaling all covariances on the h-file or by adding white noise or random-walk noise to the variances of individual stations. We discuss in Section 4.3 why the latter approach is usually preferred.

To obtain meaningful estimates of crustal motion, it is necessary to define a reference frame by imposing constraints on the solution. These come in two common flavors: With finite constraints, we assign realistic a priori uncertainties to the coordinates and velocities of one or more sites. This is the only option available in GAMIT and it is also available in GLOBK. A minimum (non-redundant) constraint with this approach would involve restricting translation by fixing or tightly constraining the three coordinates of one site, and restricting rotation by constraining Earth orientation. Constraining additional sites provides redundancy, but can distort the network and remove your ability to detect errors in those sites except through an increase in χ^2 . The second type of constraint, available through the *glorg* program of GLOBK, is generalized. With this approach, we choose as large a set as possible of sites with good a priori values and minimize their adjustments while estimating an overall translation, rotation, and scale (Helmert parameters) of the network. Since all of the frame-defining sites are free to move, outliers can be readily detected and removed. Moreover, with generalized constraints there can be no internal distortion of the network: all realizations of the reference frame with a given data set will differ only by a translation and rotation. See *Dong et al.*, [1998] for a mathematical description of each of these approaches.

2. Automatic Processing with GAMIT and GLOBK

GAMIT is composed of distinct programs which perform the functions of preparing the data for processing (*makexp* and *makex*), generating reference orbit and rotation values for the satellites (*arc*, *yawtab*), interpolating time- and location-specific values of atmospheric and loading models (*grdtab*), computing residual observations (O-C's) and partial derivatives from a geometrical model (*model*), detecting outliers or breaks in the data (*autcln*), and performing a least squares analysis (*solve*). Although the modules can be run individually, they are tied together through the data flow, particularly file-naming conventions, in such a way that most processing is best done with shell scripts and a sequence of batch files set up by a driver module (*fixdrv*) for modeling, editing, and estimation. Though the data editing is almost always performed automatically, the

solution residuals can be displayed or plotted so that problematic data can be identified (*cview*).

Likewise, GLOBK operates through distinct programs, which can be invoked with a single command or run separately. The primary functions are to combine quasi-observations--either GAMIT/GLOBK “h-files” or the internationally accepted SINEX format--from multiple networks and/or epochs (*glred* or *globk*), and to impose on this solution a reference frame appropriate to the scientific objective (*glorg*). Note that *globk* and *glred* are the same program, just called in different modes: *glred* to read data from one day at a time for generating time series, *globk* for stacking multiple epochs to obtain a mean position and/or velocity.

The full sequence of steps to take you from phase data to time series is accomplished with two shell scripts: *sh_gamit* looks for RINEX data over a range of days and invokes the GAMIT programs to produce constrained and loose estimates of coordinates together with sky plots of phase data as a record of the processing; *sh_glred* uses the GAMIT results to produce time series of day-to-day repeatability or a combined h-file that may be further combined with those from other epochs to estimate station velocities. The only preparation required is assembling the meta-data from station logs; setting up the control files, most of which are common to all analyses of a particular era; and assembling RINEX files not available from public archive in one or more directories on your system.

Note that all of the scripts and programs that use command-line control are self-documenting: to see the input commands, just type the script or program name with no arguments.

2.1 Setup

The first step in running the scripts is to create a project directory (e.g. */emed18* or */emed/2018* for data from 2018 for the eastern Mediterranean) with two subdirectories: */rinex* and */tables*. Copy into the */rinex* directory all of the local RINEX files you plan to use in your processing. GAMIT will handle either RINEX 2 or RINEX 3 formats, but the RINEX 3 files must be renamed to the 10-character RINEX 2 naming scheme (lowercase *ssssddd.yyo* and *brdcddd.yyn*; this happens automatically in *sh_gamit*). RINEX files for IGS directories to be down-loaded automatically during the processing are specified using entries in a control file (*site.defaults*) (see Section 2.3 below and Section 6.3 of the *GAMIT Reference Manual*). Then run *sh_setup* to link or copy into the [project]/*tables* directory the appropriate control and data files. All of the required templates and tables reside in *~gg/tables*, where *~gg* is a required alias pointing to the highest level of the GAMIT/GLOBK installation. Executing *sh_setup* will invoke *sh_links.tables* to link the standard data tables described in Section 4.1) and will copy the eight control and data files listed below:

`process.defaults` : Edit this file to specify your computation environment, sources for internal and external data and orbit files, start time and sampling interval, instructions for archiving the results, and an email address to receive a summary of the run.

`sites.defaults` : Edit this file to specify which local and IGS stations are to be used and how station meta-data are to be handled.

`station.info` : This file contains the receiver and antenna type and height of instrument (HI) values as a function of time for all occupations of the stations you will use. Although it can be generated during processing by `sh_gamit`, the best approach is usually to construct the file prior to processing using the tools described in Section 2.3.

coordinate files : `sh_gamit` maintains in the experiment `.tables` directory two files of a priori coordinates. The file ending in `.apr` (set as `apr` in `process.defaults`, `itr14_comb.apr` in the template) contains the Cartesian coordinates (position and velocity) of stations you wish to have unchanged throughout the processing. The L-file (`lfile.`), which can contain either Cartesian position and velocity (default, same as `.apr` file) or spherical position (GAMIT old-style, use `-oldfmt_lfile` option in `sh_setup`), is updated after each day is processed if the adjustments exceed a specified value (0.3 m by default). If you have good coordinates for stations not in the `apr` file, you should append these to the `apr`-file if you want them to be unchanged. For any station that does not have coordinates in `lfile.`, `sh_gamit` will attempt to calculate coordinates via a pseudorange solution, or (if `use_rxc Y` in `process.defaults`) use the coordinates in the RINEX header. When GAMIT runs, these coordinates will be updated in `[expf]/tables/lfile.` from the phase solution so that for successive days on which the same station is observed, the accurate coordinates will be used.

`sestbl.` and `sittbl.` : Edit these files to set the appropriate options for your analysis. Make sure that any station for which you specify tight constraints in `sittbl.` has accurate coordinates in the `apr` file.

`autcln.cmd` : Controls for cleaning the data in program `autcln`. This file will usually not require editing unless you encounter unusual data during the processing.

Once you have edited appropriately the template files, you can start the processing from within the experiment directory by giving `sh_gamit` simply the 4-character code for the project or subnet (termed “experiment”) and a range of days to process:

```
sh_gamit -expt emed -d 2018 034 035 036 >&! sh_gamit.log
```

The `sh_gamit` command is executed at the project-directory level. The time span can also be specified using `-s <start_day> <stop_day>` to indicate a range of consecutive days, or `-r <days>` to indicate that you want to process a single day `<days>` before the current date. If you plan to process data from more than GPS, use `-gnss [sys]`, where `sys` is G for GPS, R for Glonass, C for Beidou, E for Galileo, and I for IRNSS. You may also override some of the parameters specified in `process.defaults`:

```
-orbit <type>    Type of orbit (e.g. igsf igsr igsu codm gfmz siof; see sh_orbits; default igsf)
-eops <name>    EOP series to be used (usno [default], usnd)
```

-sessinfo	Sampling interval, #epochs, start time (HH MM) (e.g. 30 2880 0 0)
-copt	List of files to compress in the day directory (default x, k, autcln.out, d)
-dopt	List of files to delete from the day directory (default C-files only)
-pres ELEV	Plot phase vs elevation and as skyplots (default no)
-nogifs	Do not create gif files of sky plots (default is to create from postscript)
-yrest	Add year prefix to names of day directories
-netext <char>	Add suffix (character) to names of day directories
-noftp	Don't try to ftp any data from outside your system (default is to ftp)

Most of the time the parameters may be omitted in favor of the values you have specified in `process.defaults` for the whole experiment. The overrides are useful, however, if you wish to test the effect of processing a day with a different orbit, EOP table, or session length, or for different GNSS, in which case you can create a second directory for the same day by appending a character to its name (e.g., `-netext t` to create `/034t`). When `-gnss` is specified, the day directories will automatically be named with the GNSS code as the extent (e.g. `034E` for Galileo). Finally, you may launch `sh_gamit` from anywhere on the system by specifying the full path name of the processing directory with `-dir <path>`. When the script runs, it will write to the screen a record of each step, which you may choose to redirect to a file (e.g., `>&! sh_gamit.log`). Examining the screen log together with the comments and source code in `gg/com/sh_gamit` and the `GAMIT.fatal` file, will allow you to identify the point and reason for failure should that occur.

When processing of each day is completed, `sh_gamit` will send a mail message to you (`mailto` in `process.defaults`) giving the number of stations used, the rms of the one-way phase residuals for the two best and two worst stations from the `autcln` postfit summary file, the `nrms` values from the Q-file, the number of ambiguities resolved, and a list of any large adjustments to station coordinates. These statistics will let you know whether you need to examine the GAMIT output further for possible reprocessing.

To use `sh_glred` to obtain a time series of position estimates, you need to edit one and possibly more control files in the `/gsoln` directory established by `sh_setup`. In the simplest case, in which you want to use all of the sites in your GAMIT solutions and are not combining these solutions with h-files from an external source, you need only edit `glorg.cmd` to specify which sites will be used to define your reference frame. If you want to omit some sites or indicate where steps should be applied in the time series to account for earthquakes or changes in instrumentation, you may need to edit also `globk.cmd` and an earthquake/rename file. These are described in Section 2.3. Then run, e.g.,

```
sh_glred -expt emed -s 2018 34 2018 36 -opt H G T >&! sh_glred.log
```

The `H` option tells `sh_glred` to translate GAMIT h-files in the day directory to GLOBK binary h-files and put them into `/glbf`; `G` indicates that `glred` is to be run (you can use `sh_glred` just to do the h-file translation if you wish); and `T` indicates that time-series plots are to be generated using `sh_plot_pos` (invoking first `tssum` the program that extracts

coordinates from the *glred* output .org file to produce .pos files). Prior to Release 10.6, the coordinates could be extracted only with programs *ensum* and *multibase* to produce mb files and plotted with *sh_plotcrd*. This option is still available in 10.7 with key letter E but will be deprecated in future releases. Finally, it is possible to combine the h-files you have created in the day directories with global or regional h-files generated by an external processing center (e.g. MIT or SOPAC), using the *hfn* token in `[project]/process.defaults` (see Section 2.3).

sh_glred uses the `-netext` option with one or more GNSS (or other *netext*) codes to select which day directories to access for GAMIT h-files, appending a (lowercase) letter to the GLOBK binary h-file to distinguish among files in the *globk* `gdl` list.

2.2 Summary of program flow

To understand how to set up input controls and evaluate your solution, you need to have in mind the data and solution files produced at each step. The examples below are from the 5-station 2000 February 3rd (day-of-year 034) GPS-only southern California survey used in previous releases for testing the installation.

<u>File</u>	<u>Name example</u>	<u>Description</u>
RINEX	blyt0340.05o	RINEX observation file, input to <i>makex</i>
x-files	xblyt0.034	GAMIT ASCII observation files, similar to RINEX but the start/stop times and sampling interval are the same for all sites; output of <i>makex</i> , input to <i>model</i> .
c-files	cblyt0.034	GAMIT binary observation files, contain o-c's and partial derivatives as well as observations; output of <i>model</i> , input and output of <i>autcln</i> , input to <i>solve</i> . 6 th character increments <i>a</i> , <i>b</i> , .. in successive iterations.
q-file	qscala.034	Full solution report from <i>solve</i> ; 6 th character <i>p</i> indicates the preliminary solution, <i>a</i> the final solution.
GAMIT h-file	hscala.00034	Loosely constrained solution estimates and covariances from <i>solve</i> .
GLOBK h-file	h0002031200_scal.glx	Binary h-file for GLOBK, created by <i>htoglb</i> .
org file	globk..org	Solution report from <i>glorg</i> .

Note that GAMIT files are named with single- or two-digit years and day-of-year and have a required format, whereas GLOBK h-filenames are arbitrary but conventionally named with two-digit year, month, day, hour, and minute. A full description of the

preprocessing steps undertaken by *makexp* and *makex* to produce x-files and the coordinate, clock, and orbit files used by *model* can be found in Chapter 2 of the *GAMIT Reference Manual*; naming of c-files and a description of the q- and o-files produced by *solve* is in Chapter 3. Of the GAMIT-produced files, only the h-file has more than a one-digit year in its name since it is the only file that is carried beyond the processing for a single survey. The org file is described in Chapter 3 below.

It is also useful to have in mind the way the files containing external data, survey metadata, and command files get from their natural homes to the day directory for processing. “Global” files, which contain information useful for many surveys reside in *gg/tables* but are linked by *sh_gamit* into the project */tables* directory (script *sh_link_tables*) and then into the day directory (script *links.day*), usually under the same name. These include:

EOP tables from the IERS:	ut1. pole.
Lunar-solar ephemerides	nbody
GPST - UTC	leap.sec
IGS receiver/antenna codes	rcvant.dat
User-defined receiver/antenna codes1	guess_rcvant.dat
Ground antenna mechanical dimensions	hi.dat
Satellite block #s, PRN #s, masses	svnav.dat
Ground/SV antenna phase center models	antmod.dat
P1-C1, P1-P2 code biases	dcb.dat
Empirical ZHD & mapping functions (MF)	gpt.grid
Time- & space dependent ZHD and MF	map.grid, map.list
Ocean loading	otl.grid, otl.list
Atmospheric tidal loading	atl.grid, atl.list
Non-tidal atmospheric loading	atml.grid, atml.list

The particular version of each of these files is specified by the link in *gg/tables* or the project */tables* directory. For example, the FES2004 ocean loading model is selected by linking *otl.grid* to *otl.FES2004.grid* in *gg/tables*. For EOP tables, the source (e.g., IERS Bulletin A, coded as *usno* or *usnd*) is specified in *process.defaults* or the *sh_gamit* command line and implemented via the link in the project */tables* directory. For the non-tidal atmospheric loading (*otl.grid*) and the atmospheric delay (*map.grid*) files the link in the project */tables* directory is made to a *gg/tables* version for the appropriate year. The grid files for VMF1, atmospheric tidal loading, and non-tidal atmospheric loading may not be needed for most analyses, so their links can remain empty (see below for *sestbl* entries). ***All of these global tables need to be updated from time to time***--the EOP and the VMF1 and ATML grid files daily or weekly if you are processing in near real-time; *dcb.dat*, monthly; *leap.sec* yearly; *svnav.dat* whenever a new satellite is launched; and the receiver/antenna tables whenever new instrumentation appears. Note that with the 10.7 release the Earth and Sun positions are obtained from a 20-year tabulation, file named *nbody* which may be linked in *gg/tables* either to the MIT/CfA file *nbody740.2020.asc* used in the past to produce *soltab*. and *luntab*. for each year or to the JPL file *JPL.DE200*, which is the IGS standard. We've found no significant difference in GPS orbital accuracy between the two ephemerides and hence have created the link in *gg/tables* to the

MIT/CfA file for continuity. Nutation, which were tabulated in `nutabl` for each year from an IERS-produced subroutine, are now computed internally from the subroutine. If the `nbody` link is empty, GAMIT will revert to using `soltab.[yyyy]`, `luntab.[yyyy]`, and `nutabl.[yyyy]` which are available through 2018 but will not be created in the future.

The command files (`process.defaults`, `sites.defaults`, `sestbl`, `sittbl`, `autcln.cmd`, and the GLOBK files) are usually specific to a particular survey or processing effort, so the master version of these is usually kept in the `[project]/tables` directory or a higher-level directory common to multiple projects, each of which may pertain only to a single year's data. (It is possible to include multiple years within a single project by pre-pending the year to the day directories, but this introduces complications in linking single-year, meteorological, and loading files into the `[project]/tables` directory. When `sh_gamit` runs it will link these files into each day directory. However, if a file by the same name already exists in the day directory, it will not be removed, so if you need to have a different setting for one day (e.g. a day-specific `autcln.cmd` file), you can create it within the day directory and it will be maintained through repeated processing of that day.

The third set of files comprises those that are day-specific. These include the data files shown at the beginning of this section, but also the orbit, clock, and coordinate files created during the processing. The primary orbital information for GAMIT is the (short, ascii) `g`-file (e.g., `gigg0.034` where the 'f' for final in the `-orbt` command has been replaced by 'g' to indicate GPS), which contains for each satellite the values of position and velocity at a particular epoch (usually 12:00 on the day being processed) and coefficients of the 9-component solar radiation-pressure model. These 16 parameters are sufficient for `arc` to generate a tabular ephemeris (binary `t`-file, e.g., `tigsg0.034`) for `model` to use in computing the theoretical value of the observations. In normal processing, the `g`-file is created by `sh_gamit` (invoking `sh_sp3fit`) in the `/igs` directory by fitting `arc`'s model to an ascii tabular ephemeris (in the IGS `sp3` format) from an external source. `sh_gamit` then copies the `g`-file to the `/gfiles` directory and creates a link from the day directory to the file in `/gfiles`. This complicated procedure is useful for two reasons: 1) GAMIT requires partial derivatives of the orbital position with respect to the initial parameters in order to estimate these parameters, and these are not available on the `sp3` file; 2) the `/igs` and/or `/gfiles` directories can be used to create multiday orbits for processing pre-IGS data. The satellite clock file (e.g., `jcodr0.034` or `jbrdc0.034`) and receiver clock files (e.g., `kblyt0.034`, `lscal0.034`) all exist solely within the day directory. A description of each of these files may be found in Chapters 1 and 2 of the *GAMIT Reference Manual*. The master coordinate file for the survey is named `lfile` and kept in the project `/tables` directory. When `sh_gamit` runs it makes a day-specific link, e.g. `lscal0.034` within each day directory, where updates are made by after each of the two solutions and given the names, e.g., `lscala.034` and `lscalb.034`. We discuss in Section 2.4 the rules for updating `./tables/lfile`.

2.3 Editing the control files

Program flow within `sh_gamit` and `sh_glred` is controlled by `process.defaults`, shown below with annotations added for each section:


```

## LOCAL DIRECTORIES
# Directory for translation of raw data (may have links to /rawfnd)
set rawpth = "/data13/simon/mitnet/raw"
# Directory path for raw archives (search all levels); e.g. /data18/simon
set rawfnd = ""
# Input files for RINEX translators
set mpth = "$procdir/mkrinex"
# RINEX files directory
set rpth = "$procdir/rinex"
# Directory path for RINEX archives (search all levels); e.g. /data18/simon
set rnxfnd = ""
# Directory for RINEX navigation files (Broadcast orbits)
set bpth = "$procdir/brdc"
# IGS files directory
set ipth = "$procdir/igs"
# Directory for g-files
set gpth = "$procdir/gfiles"
# GAMIT and GLOBK tables directory
set tpth = "$procdir/tables"
# Globk solution directory
set glbpth = "$procdir/gsoln"
# Globk binary h-file directory
set glfpth = "$procdir/glbf"
# Output directory for skyplots (converted from ps to gif to save space)
set gifpth = "$procdir/gifs"
# Place to store temporary control files
set cpth = "$procdir/control"
# Archive root directory (cannot be null even if not used)
set archivepth = "$procdir/archive"

```

This first section simply names the directories to be used for the processing. Most of the directories will be created with these names whether or not you include the entry and whether or not you actually use the directory. The only entry you are likely to change is `glbpth`, for which you may want to assign successively different directory names (e.g., `gsoln`, `hsoln`, `tsoln`) if you perform parallel *sh_gfred* solutions using, for example, different combinations of data.

```

## GAMIT
# Set sampling interval, number of epochs, and start time for processing
set sint = '30'
set nepc = '2880'
set stime = '0 0'
# Variables for updating station.info tables (see sh_upd_stnfo)
set stinf_unique = "-u"
set stinf_nosort = "-nosort"
set stinf_slthgt = "2.00"
# Set "Y" to use RINEX header coordinates if not in lfile or apr file
set use_rxc = "N"
# 4-character code for broadcast orbits
set brdc = 'brdc'
# Set the ftp archives to be searched for RINEX files
set rinex_ftpsites = ( sopac cddis unavco )
# Minimum x-file size to be processed (Def. 300 blocks)
set minxf = '300'
# Set search window for RINEX files which might contain data for day
set rx_doy_plus = 1
set rx_doy_minus = 1

```

```

# Default apr file for sh_gamit
set aprf = igs14_comb.apr
# Set compress (copt), delete (dopt), an archive (aopt) options
set copt = ( x k ao )
set dopt = ( c )
set aopt = " "

```

The session variables are set here by default but can be overridden with the `-sessinfo` option on the `sh_gamit` command line. They specify, respectively, the sampling interval, number of epochs (2880 is 24 hr at 30s intervals), and the start time (hr min). The next four entries allow you to control how `station.info` and the L-file are updated. They work with `sites.defaults` entries and are explained in the next section. The `rinex_ftpsites` option specifies what remote archives are to be searched for RINEX files; you may add archives of your choosing by editing `gg/tables/ftp_info`. The minimum x-file size option allows you to exclude from GAMIT processing data from sessions too short to be useful for your application. The 300-block (300 Kb on most machines) default sets the limit at about 3 hours of tracking; change this to a small number to process short sessions. The search window options instruct `sh_gamit` to look for RINEX files named with day-of-year different from the one being processed. This assures that you will not miss local data within a file named for a previous day (`rx_doy_minus`), and for midnight-crossing sessions, that you will ftp and include IGS data from the part of the session on the following day (`rx_doy_plus`). The `rx_doy_minus` option may need to be increased if you have RINEX files covering many days (the GAMIT maximum is 7). Changing these to 0 will save a little time if you know that all of your data are within the expected 0-24h span. Both of these options can be specified in the `sh_gamit` command line if you want to change them on a day-to-day basis.

```

## RESOURCES
# Minimum raw disk space in Kbytes
set minraw = '30000'
# Minimum RINEX disk space in Kbytes
set minrinex = '30000'
# Minimum archive disk space in Kbytes
set minarchive = '20000'
# Minimum working disk space in Kbytes
set minwork = '200000'

```

The resource settings prevent processing from starting if there is inadequate disk space to complete it.

```

## OPERATING-SYSTEM-DEPENDENT SETTINGS
# UNIX df command to return free space in kilobytes
set udf = 'df -k'
# old HP
# set udf = 'bdf -k'
# UNIX mail command to allow subject in the command line
set umail = 'mail -s'
# old HP
# set umail = 'mailx -s'

```

```

# Mail address for the processing report (if null will default to #
`whoami` in sh_gamit)
set mailto = ' '
# Host name for email and anonymous ftp password use
# (if null will default to `hostname` in sh_gamit)
set machine = ' '
# Ghostscript path
set gspath = '/usr/bin'
# ImageMagick path for `convert`, used for gif conversion
set impath = '/usr/bin'
# set impath = '/usr/bin/X11'

```

The only system-dependent setting likely to need changing is the path for the *convert* program, used to convert the sky plots from postscript to png. If your UNIX installation does not have *convert* available, use `-nopngs` in the *sh_gamit* command line so that the sky plots will be left as postscript in the day directory

The `site.defaults` file determines how each station will be used in the processing. Since all sites in your `/rinex` directory will be automatically included in your processing, in most cases you need to list here only those sites for which you want to automatically download data from a remote archive (`ftprnx` token). This assumes that you do not want to include or exclude individual sites from automatic updating in `station.info` (`xstinfo` token) or to exclude from processing sites for which you have RINEX files in the `/rinex` directory (`xsite` token). Note that you must include after each site name the 4-character “experiment” name you use in your processing (shown in the example below as `scal`). This requirement derives from the feature to allow `site.defaults` to select sites to be used in each of several sub-networks when you are processing multiple sub-networks.

```

# File to control the use of stations in the processing
#
# Format: site  expt  keyword1  keyword2  ....
#
# where the first token is the 4- or 8-character station name;
# the second token is the 4-character experiment name,
# and the remaining tokens, read free-format, indicate how the station is
# to be used in the processing. All stations for which there are RINEX
# files in the local directory will be used automatically in the GAMIT
# processing and do not need to be listed.
#
# ftprnx = sites to ftp from rinex data archives.
# ftpraw = sites to ftp from raw data archives.
# xstinfo = sites to exclude from automatic station.info updating.
# xsite = sites to exclude from processing, all days or specified days
#
all_sites scal xstinfo
blyt_gps scal ftprnx
jplm_gps scal ftprnx
math_gps scal ftprnx
# ttth_gps scal xstinfo xsite:1999_256-1999_278

```

The `xsite` option can also be used on the *sh_gamit* command line.

The processing within GAMIT itself (*arc, model, autcln, solve*) is controlled by *sestbl.*, *sittbl.*, and *autcln.cmd*. The *sestbl.* entries that you are likely to consider in setting up your processing are shown below:

```

Choice of Experiment = BASELINE.      ; BASELINE/RELAX./ORBIT
Satellite Constraint = N ; Y/N ( N ignores the next two lines, giving constraints in ppm
and %)
  all  a    e    i    n    w    M    rad1  rad2  rad3  rad4  rad5  rad6  rad7  rad8. rad9
      0.01 0.01 0.01 0.01 0.01 0.01 1     1     .1   .1   .1   .1   .1   .1   .1

Choice of Observable = LC_AUTCLN    ; LC_HELP/L1_ONLY/L2_ONLY/LC_ONLY/L1_RECEIVER/L1,L2_INDEP
Ambiguity resolution WL = 0.15 0.15 1000. 99. 15000.; increase chi-sq ratio to stop search
Ambiguity resolution NL = 0.15 0.15 1000. 99. 15000.; set dist = 500. for LC_HELP
Ionospheric Constraints = 0.0 mm + 8.00 ppm; set for mid-solar max -used only for LC_HELP
D
Map = GMF                          ; GMF(default)/NMFH/VMF1
WMap = GMF                          ; GMF(default)/NMFH/VMF1
Map.grid = Y                        ; YES/NO (default NO)
Met obs source = GPT 50             ; hierarchical list: RNX UFL GPT/STP [humid value]
Zenith Delay Estimation = YES      ; YES/NO
Interval Zen = 2                   ; zenith-delay parameters at 2-hr-intervals
Zenith Variation = 0.02 100.       ; zenith-delay variation, tau in meters/sqrt(hr), hrs
Elevation cutoff = 0.              ; elevation cutoff for SOLVE; default 0 to use autcln cutoff
Atmospheric gradients = YES       ; YES/NO (default no)
Number gradients = 2               ; number of gradient (E/W or N/S) parameters) (default 1)
Gradient Constraints = 0.01        ; gradient at 10 deg elevation in meters
Gradient Variation = 0.01 100.    ; gradient variation, tau in m/sqrt(hr), hrs (default .01 100)
Output met = N                     ; write the a priori met values to a z-file

Update T/L files = L_ONLY          ; L_ONLY (default), T_AND_L , T_ONLY, NONE

AUTCLN Command File = autcln.cmd    ; filename; default none (use default options)
Station Error = ELEVATION 10. 0.0001 ; a**2 + b**2/sin(elev)**2 in mm, default = 4.3 7.0

Decimation Factor = 4              ; decimation factor in solve
Quick-pre observable = LC_ONLY     ; for 1st ('prefit) soln; default same as Choice of Observ
Quick-pre decimation factor = 10   ; autcln pre, default same as Decimation Factor

Antenna Model = ELEV              ; NONE/ELEV/AZEL default = NONE
Tides applied = 31                ; Binary: 1 earth (2 K1 for IERS92)) 4 pole 8 ocean loading
                                   16 remove mean pole 32 atm; default = 31
Use otl.list = N                  ; Station-list file for ocean tidal loading (default N)
Use otl.grid = Y                  ; Global grid file for ocean tidal loading (default N)

```

The values shown are appropriate for regional or global processing for most data acquired after 1995. By setting **Choice of experiment = BASELINE**, you are fixing the orbits and omitting the orbital parameters from your GAMIT processing and output h-files. If you intend to combine your h-files with those from global processing at, e.g., MIT or SOPAC, or if you are processing a GNSS with poor orbits, then you should set **Choice of experiment = RELAX** and apply constraints to the orbital parameters. The values given for orbital parameters (1 part in 10^9 or about 2 cm) are reasonable for current IGS orbits (see <http://acc.igs.org> for orbital accuracy over time).

The next four entries control the observations used and ambiguity resolution. **LC_AUTCLN** and **LC_HELP** are the usual choices with dual-frequency receivers and all but the shortest baselines. With the **LC_AUTCLN** option, the widelane ambiguities are assigned and resolved in *autcln* using the pseudoranges. With **LC_HELP**, the wide-lane ambiguities are

resolved by applying an ionospheric constraint (see *Dong et al.*, 1998). For data acquired with codeless receivers (before ~1994), `LC_HELP` should be used. The sensitivity parameters for both wide-lane (with `LC_HELP`) and narrow-lane ambiguities are set conservatively but may be varied if you need to squeeze greater accuracy out of short observing sessions. See *Dong et al.* [1998] and Section 3.5 of the *GAMIT Reference Manual* for a detailed discussion. For baselines less than a few km, using L1 and L2 independently or only L1 may reduce noise compared to using the ionosphere-free combination. To check for the size of ionospheric errors, it's wise to try `LC_HELP`, `L1_ONLY`, `L2_ONLY`, and `L1,L2_INDEP` and compare the results. If your data were acquired with a single-frequency receiver, you should set `L1_RECEIVER` in the `sestbl`. and also add the `L1only` command to `autcln.cmd` since `autcln` by default will attempt to use both L1 and L2 in cleaning (even if `L1_ONLY` is requested for `solve`).

The next block of entries controls the modeling and estimation of the atmospheric delay. The first command specifies the mapping function to be used to project the zenith delay to the elevation angle of the satellites. Different functions must be used for the hydrostatic (“dry”) delay and the “wet” delay due to water vapor. The default, sufficient for all but the most accurate studies of heights and for meteorological studies, is the “global mapping function” (GMF) developed by *Boehm et al.* [2006a] from fitting numerical weather model (NWM) data over 20 years. A more accurate reconstruction of the NWM data can be obtained by interpolating hydrostatic and wet mapping function coefficients as a function of time and location from the (large) global grid files compiled by the Vienna group [*Boehm et al.*, 2006b]. You have access to these values by downloading the VMF1 grid files for each year from `pub/GRIDS` on `everest.mit.edu`, and setting `map.grid = Y`, `DMap = VMF1` and `WMap = VMF1`. The next command controls the source of pressure (most importantly, but also temperature) for the a priori zenith hydrostatic delay (ZHD). The most accurate values, if they are available, are from local measurements of surface pressure, which can be written into RINEX met files and stored in a `/met` directory for use by `sh_gamit`. Setting the first option of `Met obs source = RNX` tells GAMIT to use these for any station for which they are available. The next most accurate source would be the ZHD values from the VMF1 grid files. Since GAMIT reads the grid file for all sites used for the day and writes the values into the U-file, you select this option by setting `Met obs source = UFL` and `map.grid = Y`. (If you use a VMF1 station-list file, `map.list`, the second option, `GPT` or `UFL` can be used for stations missing from the list file. Since the only source of NWM ZHD data currently tabulated for GAMIT is the VMF1 mapping-function grids, the `met.grid` and `met.list` files are not yet supported.) Finally, as with the mapping functions, the Vienna group has constructed from the NWM data an analytical model, designated “global pressure and temperature” (GPT2), of *Lagler et al.*, *Geophys. Resl. Lett.* 40, doi:10.1002/grl50288, 2013). It reads from table `gpt.grid` in `~/gg/tables` values of zenith hydrostatic delay (ZHD), temperature, lapse rate, and dry and wet mapping functions as a function of latitude, longitude, and day-of-year that are averages from a fit to 10-year monthly averages from a global numerical weather model. The option `STP` implies standard constants (1013.25 hPa, 20 C), used prior to Release 10.3 but now effectively obsolete. To keep errors in height estimates below 2 mm, you need an accuracy of about 10 hPa in a priori pressure [*Tregoning and Herring*, 2006]. The `Interval zen` command controls the

number of zenith delay parameters estimated using the session. For geodetic studies, estimating values at 2-hour intervals with the constraints given is more than adequate. For meteorological studies, you may want to estimate more parameters and/or alter the constraints (*see Chapter 7 of the GAMIT Reference Manual*). For atmospheric gradients, we allow a linear change during the session (two parameters each for N/S and E/W gradients).

The command to update the L-file assures that the second *solve* solution will have adjustments within a linear range and allows *sh_gamit* to apply updated coordinates to the processing of successive days. The criterion for updating is set by default to be adjustments larger than 30 cm (though this can be changed with a *sestbl* command, not shown). If you know that all of your a priori coordinates are accurate to within a few cm and don't want bad data to corrupt the coordinates in the L-file, you can set `Update T/L files = NONE`.

The next three commands control how the phase data are weighted in the preliminary and final solutions. The **Station Error** entry shown tells *solve* to use elevation-dependent weighting for the phase data. In the preliminary solution, the assigned error is 10 mm with negligible elevation dependence. With **AUTCLN postfit = Y** (default with **Type of analysis = 1-ITER**) the second *solve* run will assign weights to the phase data based on the actual scatter computed by *autcln* in its "postfit" edit, and will contain both a constant and an elevation-dependent term, as recorded in the output print file *autcln.post.sum*. Elevation-dependent weighting is recommended for almost all analyses; an exception might be tests of models (e.g. mapping functions) sensitive to low-elevation observations.

Related to the error weighting is the sampling of data for the solution. For cleaning purposes (*model*, *autcln*), the full sampling of the x-file (usually 30s or 15s) is used. However, since the phase errors are correlated over many minutes, it is not necessary to use sampling this frequent in *solve*. The default decimation factor (4, resulting in 2-minute sampling for the usual case) provides formal uncertainties that are usually reasonable within a factor of two while reducing time significantly (See the discussion of uncertainties in Section 1.3.) For the preliminary solution used to get decimeter-level coordinates for editing and to avoid non-linearity in the final adjustments, 5-minute sampling is sufficient.

There are over a dozen *sestbl* entries controlling the models used in processing the data. These are all given at the bottom of the template file in *gg/tables* and discussed in Section 3.2 of the *GAMIT Reference Manual*. The three shown here are those most likely to need editing for current applications. Changing **Antenna Model** to **NONE** allows bypassing of the phase-center-variation (PCV) file *antmod.dat*, an option advisable only if you are using identical antennas within a small regional network. The **Tides applied** option is binary coded, allowing any combination of the various tidal models to be applied in *model*. For most applications you may keep the default, which is to apply all of the tidal effects currently available in GAMIT (though the 2-bit for K1 is not necessary with the current IERS 2003 model for the solid-body tides, and the pole tide can be applied later in GLOBK). If your data are not strongly affected by ocean tidal loading ("otl") or you do not wish to copy over the large ocean loading grid files, you might omit this model,

setting `Tides applied = 23` instead of 31. The `otl` components are read from a station list file or a global grid, with station-list values taking precedent if `Use otl.list = Y` and the station is within 10 km of a station in the file. If you have local stations close to an IGS station, it is advisable to use the grid exclusively so that you don't introduce artifacts in the relative motions of two stations.

The `sittbl.` contains options that can be set on a station-by-station basis. The width of the table is variable, with the entries determined by the column headers present. A complete version is available as `gg/tables/sittbl.long`, but the short version shown below contains the only entries you are likely to change—the a priori station constraints to be applied in GAMIT to enhance ambiguity resolution and to obtain a solution that you can inspect visually (this assumes that your final solution will come from GLOBK).

```

SITE                --COORD.CONSTR.--
      << default for regional stations >>
ALL                100.  100.  100.
      << Stations to constrain >>
BLYT Blythe_       0.010 0.010 0.02
JPLM JPL Mesa     0.010 0.010 0.02
MATH Lake Matthews 0.010 0.010 0.02

```

The 4-character site name must appear in the first four columns, the 12-character name is of arbitrary length beneath a blank header, and the coordinate constraints are free-format but must fall within the columns denoted by the header `--COORD.CONSTR.--`. The constraints are north, east, and up in meters.

The remaining control file for GAMIT is `autcln.cmd`. It is complicated but can almost always be left unchanged. Cases for which you might want alter the default settings include data from codeless receivers, stations for which you cannot get a priori coordinates better than 10 m, or short sessions ($< \sim 3$ hours). For a detailed discussion of the `autcln` settings, see Section 4.2 of the *GAMIT Reference Manual*.

There are two required control files for `sh_glred`. The names `globk.cmd`, and `glorg.cmd` are set by the script but can be overridden with the command line options `-globk_cmd` and `-glorg_cmd`. Unlike the GAMIT `sestbl.` and `sittbl.`, which for which entries must begin in column 1, all GLOBK files, as well as the `sh_gamit` control files `process.defaults` and `site.defaults`, follow the convention that a non-blank first column denotes a comment (* or # below in the examples below) except that you can specify (arbitrary) keywords beginning in line 1 that match the `<OPTIONS>` list at the end of the `globk/glred` command line. If the keyword is given as an option, `globk/glred` will replace the keyword in the command file by a blank, thus activating the command. For example, with the command file shown below

```
sh_glred -expt emed -s 2018 34 2018 36 -ncomb 3 -globk_prefix COMB -opt G
```

will will transform the command file from one appropriate for time series (solution for each day) one that will stack all of the days together and create a combined h-file for the period of the survey.

```

* globk/glred command file for time series, short-term combinations
* and velocity solutions
* Set COMB as a globk command line option for short-term combinations;
* since these commands follow the commands for repeatabilities, they
* will take precedence when invoked.
* Set VEL as a globk command-line option for velocity; since these
* commands follow the commands for repeatabilities, they will
* take precedence when invoked.
* Set KEEP to allow glorg to be run separately after run; useful
* for testing as a globk command-line option.
* Any combination, e.g. COMB+KEEP or VEL+KEEP will use both (or more)
* options.
* Lasted edited 180601

* << column 1 must be blank if not comment >>

* Use wild-cards in file names so that parallel runs do not overwrite
* each other. The "@" symbol is replaced with the .gdl-file name root.

* This group of commands must appear before any others:

  eq_file ~/gg/tables/igs14_comb.eq
ITRF08 eq_file ~/gg/tables/itrf08_comb.eq
# Optionally add a second eq_file for analysis-specific renames
x eq_file my_eq_file.eq

# For time-series runs, it's faster not to use the "com_file" command
# (com_file need not be created; only needed if glorg or glsave are
# to be run by themselves after globk completes).
* This group of commands must appear before any others:
KEEP com_file @.com ! Allows parallel runs
  srt_file @.srt
  srt_dir +1

# Normally for combined files, make_svs is not needed. Only needed if
# orbits are to be estimated.
x make_svs @.svs A

* End of commands that must appear first

* Solution file pointed to by the com file, if used
VEL sol_file @.sol

* ITRF 2014 augmented by now-defunct sites and recent IGS solutions;
* matched to igs14_comb.eq (ITRF2014; default)
apr_file ~/gg/tables/igs14_comb.apr
ITRF08 apr_file ~/gg/tables/itrf08_comb.apr
# Optionally add additional apr files for other sites

# Do not used an a priori rotation file with multi-day H-files
x in_pmu ~/gg/tables/pmu.usno

* Set maximum chi2, prefit coordinate difference (m), and rotation
* (mas) for an h-file to be used;
  max_chii 13 3 100

```



```

# increase tolerances to include all files for diagnostics
x max_chi 100 5.0 20000

* Correct the pole tide when not compatible with GAMIT.
* Use caution here is binary hfiles from SINEX are used since these
* file do not contain status of pole tide correction.
  app_ptid all

* Invoke glorg
  org_cmd glorg.cmd

* Print file options
  crt_opt NOPR
  prt_opt NOPR GDLF CMDS
  org_opt PSUM CMDS GDLF FIXA RNRP
VEL org_opt ERAS PSUM CMDS GDLF VSUM FIXA RNRP
# The output .org-file will be generated from the
# .prt-file name from the globk command line
# sh_glred will name the glorg print files
# To set an explicit name for the glorg print file
# globk print file name from the globk command line
x org_out glred_-----.org
xVEL org_out globk_-----.org

* Coordinate parameters to be estimated and a priori constraints
  apr_site all 10 10 10 0 0 0
VEL apr_site all 10 10 10 1 1 1

* Rotation parameters to be estimated and a priori constraints
  apr_wob 10 10 1 1
  apr_ut1 10 1
# EOP tight if translation-only stabilization in glorg (also comment out
mar_wob, mar_ut1)
x apr_wob .25 .25 .1 .1
x apr ut1 .25 .1
* For multiday combinations allow EOP's to change between days.
* The rate terms here depend on nature of gamit solutions:
* For RELAX. solutions, EOP rates are estimated and when combined
* with daily MIT .GLX-files, the rates are allowed to change and
* will be jointly estimated between the MIT and local file. When
* baseline processing is used, the rates would only apply to MIT
* files.
COMB mar_wob 3650 3650 365 365
COMB mar_ut1 365 365
VEL mar_wob 3650 3650 0 0
VEL mar_ut1 365 0

# Allow translation and scale variations for pre-1995 data and
# for data analyses that feature a a change in SV PCVs (e.g.
# operational, pre-repro1 MIT or SOPAC h-files before Week 1400, Nov
2006)
x apr_tran 1 1 1 0 0 0
xVEL apr_tran 1 1 1 1 1 1
xVEL mar_tran 3.65 3.65 3.65 0 0 0
SCALE apr_scale 10 0
xVEL apr_scale 10 1.

```

```

xVEL mar_scale 365 0

* If orbits free in GAMIT (RELAX.) and you want them fixed, use:
x apr_svs all F F F F F F FR
* but if you are combining with globk h-files, better to leave them
* on but, if the models are incompatible, turn off radiation-pressure
* parameters,
x apr_svs all 100 100 100 10 10 10 OR

* When using MIT GLX files, which have satellite phase center positions
* estimated, fix antenna offsets to IGS a priori values by using:
  apr_svan all F F F

* When combining multiple h-files from the same epoch,
* estimate atmospheric zenith delay at common sites
  apr_atm common 1
COMB mar_atm common 3.65
VEL mar_atm common 3.65

* Optionally put a uselist and/or sig_neu and mar_neu reweight in
* a source file
x source ../tables/uselist
x source ../tables/monthly_reweights

* Turn off quake log estimates if in the eq_file
  free_log -1

* Write out a combined H-file
# Can substitute your analysis name for 'COMB' in the file name below
COMB out_glb H-----_COMB.GLX
VEL out_glb @.GLX

* Remove scratch files for repeatability and combination runs
  del_scra yes
KEEP del_scra no

```

The first group of commands define files used by *gred/globk* and which must be listed first in the command file in order for the program to work properly. For time-series computations, all but the `eq_file` can be considered scratch files. The `eq_file`, described below, allows you to exclude sites or to rename them to account for breaks due to earthquakes or instrument changes.

The next two entries specify the a priori files to be used for Earth orientation and coordinates. If these are omitted, the values will be taken from the h-file (i.e., the GAMIT solution), which may be ok in many circumstances.

The `max_chi` command allows automatic removal of an h-file when the data are bad, detected in *globk* by checking for a high chi-square, a large adjustment of coordinates from their a priori values, or a large rotation of the network. For a network less than 10 km in extent, it may be necessary to loosen these values since the rotation will not be well determined.

Including the name of the *glorg* command file (`org_cmd glorg.cmd`) tells *globk* to call *glorg* for frame definition (“stabilization”) after *globk* is run. The `org_opt` command prescribes what is included in the *glorg* print summary (“org” file). `PSUM` means a summary of position adjustments; `GDLF` means to list the name of the input h-file; and `CMDS` means to echo both the *globk* and *glorg* command files. If you are invoking *glorg*, then the *globk* print will not be very useful and is suppressed by `prt_opt NOPR`.

Commands of the form `apr_` serve both to tell *globk* to estimate the parameter and to specify the a priori constraint to be used. If you are stabilizing by estimating both translation and rotation in *glorg* (the usual case with a robust network), then both the coordinate (`apr_neu`) and EOP (`apr_ut1 apr_wob`) constraints should be loose, as shown above. If you estimate only translation in *glorg*, preferable for less than four stations or a network less than 1000 km in extent, then you should tightly constrain EOP (and orbits). To apply finite constraints instead (not recommended), set the `apr_neu` values as appropriate for each station and do not invoke *glorg* (comment out the `org_cmd` line).

Sites to include in the solution are selected or deselected with the `use_site`. The default is to include all sites in the h-file(s), but you can command a subset by starting the list with `clear` followed by the site names, either four characters (all 8-character versions of the site) or the full eight (to select only certain versions); listing the site preceded by a minus will remove it from the list. In the example we've referred to a separate file (`./tables/uselist`) rather than include the `use_site` commands in the main command file. For site selection from an h-file of global processing, you can invoke the `use_pos` to include or exclude sites within a geographical region (See the *globk* help file or Section 3.1 of the *GLOBK Reference Manual*.)

The `out_glb` command, when invoked, tells *globk* to write the solution out in the form of an h-file. This is useful for aggregating data in weekly or monthly averages and/or combining your own processing with global or regional h-files from an external source (see Chapter 4).

If you need to provide for step changes in coordinates (or velocities) and/or to exclude sites during certain periods, you can use an “earthquake-rename” file (`eq_file`) with *globk*. The file has two types of entries. The first renames sites (creates new logical sites for *globk*) automatically based on their proximity to an earthquake:

```
# November 3, 2002, UT=22:12 Lat = 63.52 Lon -147.53 Depth=5 km M 7.9
eq_def DN 63.52 -147.53 700 5. 2002 11 3 22 12
eq_cosei DN 1.0 1.0 1.0 1.8 1.8 0.7
eq_post DN 100 0.1 0.1 0.1 1.8 1.8 0.7 Postseismic: 0.1 mm**2/day
eq_rename DN
```

With the lines above included in the `eq_file`, all sites within 700 km of the 2002 Denali (Alaska) earthquake will be renamed (`_gps` → `_gdn`) for h-files with start and stop times later than 22:12 on 3 November 2002. The `eq_cosei` and `eq_post` commands prescribe

the constraints applied to the co-seismic and post-seismic changes. (See the *globk* help file and Section 3.1 of the *GLOBK Reference Manual*.) The second type of command renames sites according to explicit instructions to account for changes in data quality or instrumentation:

```
rename mate_gps mate_lps          1999 6 18 0 0
rename kit3_gps kit3_xcl          1997 5 14 0 0  1997 5 18 0 0
rename madr_gps madr_xhi  emed    1996 9 26 0 0  1996 10 27 0 0
```

The first of these lines accounts for a position change with the introduction of a new receiver at Matera; the second removes some bad data at Kitab for a four-day period; the third accounts for the use of an incorrect antenna height in h-files whose names include the substring “emed”. You may use the *equate* feature of *glorg* to force the horizontal adjustments for *madr_gps* and *madr_xhi* to be the same (see Chapter 4). It is also possible to use the *rename* command to shift the position of a site without introducing a new site, useful to apply offsets known from local measurements or assumed from an earthquake model:

```
rename tigr_gni tigr_gni 2001 2 28 0 0  2100 1 1 0 0  0.0032 0.0033 0.0000 NEU
```

The entry applies 3 mm offsets of the north and east coordinates of the site based on an a priori model for the Nisqually (NI) earthquake near Seattle, Washington. For ITRF sites the *igs14_comb.eq* file provides a set of renames consistent with the *igs14_comb.apr* file (similarly *itrf08_comb.eq* and *itrf08_comb.apr*).

The *glorg* command file (*glorg_comb.cmd*) has the form:

```
* glorg command file for time series, short-term combinations and
* velocity solutions
* Set VEL as a globk command-line option for velocity; since these
* commands follow the commands for repeatabilities, they will take
* precedence when invoked.
* Add choice of plate for final reference frame (e.g. EURA14 for
* Eurasia defined by Altamimi et al.'s (2017) ITRF2014 plate motion
* model, NOAM08 for North America defined by Altamimi et al.'s (2012)
* ITRF2008 plate motion model, NA1214 for North America defined
* by Blewitt et al. (2013) using rotated ITRF2014 velocities, etc.

* Last edited by MAF 180519

* << column 1 must be blank if not comment >>

* Parameters to be estimated
pos_org  xtran ytran ztran xrot yrot zrot
VEL rate_org  xtran ytran ztran xrot yrot zrot
# Optionally, if estimated scale in GLOBK:
SCALE pos_org  xtran ytran ztran xrot yrot zrot scale
xSCALE rate_org  xtran ytran ztran xrot yrot zrot

# or if translation-only
```

```

x pos_org  xtran ytran ztran
xVEL rate_org  xtran ytran ztran

* Downweight of height relative to horizontal (default is 10 10)
# Heavy downweight if reference frame robust and heights suspect
x cnd_hgt  1000 1000

* Controls for removing sites from the stabilization
# Vary these to make the stabilization more robust or more precise
stab_it  4 0.8 3.0
x stab_it  4 0.5 4.0

* A priori coordinates to define the analysis reference frame
apr_file ~/gg/tables/igs14_comb.apr
ITRF08 apr_file ~/gg/tables/itrf08_comb.apr

# ITRF2014 plate motion model as defined by Altamimi et al. (2017)
AMUR14 apr_file ~/gg/tables/igs14_comb_amur08.apr
ANTA14 apr_file ~/gg/tables/igs14_comb_anta.apr
ARAB14 apr_file ~/gg/tables/igs14_comb_arab.apr
AUST14 apr_file ~/gg/tables/igs14_comb_aust.apr
CARB14 apr_file ~/gg/tables/igs14_comb_carb08.apr
EUR14 apr_file ~/gg/tables/igs14_comb_eura.apr
INDI14 apr_file ~/gg/tables/igs14_comb_indi.apr
NAZC14 apr_file ~/gg/tables/igs14_comb_nazc.apr
NOAM14 apr_file ~/gg/tables/igs14_comb_noam.apr
NUBI14 apr_file ~/gg/tables/igs14_comb_nubi.apr
PCFC14 apr_file ~/gg/tables/igs14_comb_pcfc.apr
SOAM14 apr_file ~/gg/tables/igs14_comb_soam.apr
SOMA14 apr_file ~/gg/tables/igs14_comb_soma.apr
SUND14 apr_file ~/gg/tables/igs14_comb_sund08.apr
# North America as defined by Blewitt et al. (2013)
NA1214 apr_file ~/gg/tables/igs14_comb_na12.apr
# Nubia and Somalia as defined by Saria et al. (2013)
NU1314 apr_file ~/gg/tables/igs14_comb_nu13.apr
SO1314 apr_file ~/gg/tables/igs14_comb_so13.apr

# ITRF2008 plate motion model as defined by Altamimi et al. (2012)
AMUR08 apr_file ~/gg/tables/itrf08_comb_amur.apr
ANTA08 apr_file ~/gg/tables/itrf08_comb_anta.apr
ARAB08 apr_file ~/gg/tables/itrf08_comb_arab.apr
AUST08 apr_file ~/gg/tables/itrf08_comb_aust.apr
CARB08 apr_file ~/gg/tables/itrf08_comb_carb.apr
EUR08 apr_file ~/gg/tables/itrf08_comb_eura.apr
INDI08 apr_file ~/gg/tables/itrf08_comb_indi.apr
NAZC08 apr_file ~/gg/tables/itrf08_comb_nazc.apr
NOAM08 apr_file ~/gg/tables/itrf08_comb_noam.apr
NUBI08 apr_file ~/gg/tables/itrf08_comb_nubi.apr
PCFC08 apr_file ~/gg/tables/itrf08_comb_pcfc.apr
SOAM08 apr_file ~/gg/tables/itrf08_comb_soam.apr
SOMA08 apr_file ~/gg/tables/itrf08_comb_soma.apr
SUND08 apr_file ~/gg/tables/itrf08_comb_sund.apr
# North America as defined by Blewitt et al. (2013)
NA1208 apr_file ~/gg/tables/itrf08_comb_na12.apr
# Nubia and Somalia as defined by Saria et al. (2013)
NU1308 apr_file ~/gg/tables/itrf08_comb_nu13.apr
SO1308 apr_file ~/gg/tables/itrf08_comb_so13.apr

```

```

# Use a regional stablization if available from a prior solution
(comment out the itrff08 file)
x apr_file ../tables/regional.apr

* List of stabilization sites
# This should match the well-determined sites in the apr_file
stab_site clear
x source ~/gg/tables/igs14_hierarchy.stab_site
source ~/gg/tables/igs14_comb.stab_site
xITRF08 source ~/gg/tables/igb08_hierarchy.stab_site
ITRF08 source ~/gg/tables/itrff08.stab_site
# Use a regional stabililization if available from a prior solution
x source ../tables/regional_stab_site

* Estimate rotation (Euler) vectors to be used with sh_org2vel to
* to rotate the solution to a block- or region-specific reference frame
xVEL plate eurasia kosg_2ps onsa_2ps nyal_4ps graz_2ps tlse_2ps
kit3_2ps
xVEL plate eurasia vill_3ps mars_3ps cbre
xVEL plate weura kosg_2ps tlse_2ps vill_3ps mars_3ps
xVEL plate aegean milo kyra xris dioa leon mkn2 bodr roml omal koun
seva
# Constrain the center-of-mass to the apr-file in plate estimate
(comment out for global solutions)
xVEL NOPLATETRAN

* Equate the velocities of co-located sites
VEL eq_dist 1000 ndot
VEL eq_dist 1000 edot
VEL eq_dist 1000 udot

* Equate a few horizontal velocities for sites farther apart
VEL equate trab_gps ndot akto_gps ndot
VEL equate trab_gps edot akto_gps edot

* Unequate velocities that are incompatible
VEL unequate mad2_gps ndot
VEL unequate mad2_gps edot
VEL unequate mad2_gps udot

```

Frame definition (stabilization or spatial filtering) is accomplished in *glorg* by specifying a set of sites for which the a priori coordinates are known at the level you expect the frame to be defined (usually 1-2 mm horizontal, 2-5 mm vertical) and the parameters you want to estimate in order to minimize the coordinate adjustments for these sites. If an apr file is included in the *glorg* command file, its coordinates will supersede those used in GAMIT or *globk*, so it is not necessary to use the same a priori coordinates for all three programs. For *glorg*, the only coordinates that matter are those for the stabilization sites. The `pos_org` command specifies the parameters to be estimated, either translation only (omit the last three entries) or translation and rotation. The rules for `stab_site` are the same as those for `use_site` in the *globk* command file. See Section 4.4 for a more comprehensive discussion of reference frame definition.

The next two entries in the file control the weighting of the quasi-observations (site coordinates) in the stabilization. For `cmd_hgtv` the first two values specify (for position and velocity, respectively) the down-weighting of heights relative to horizontal coordinates. The default is 10, under the assumption that the uncertainties in heights are about three times higher than for the horizontal coordinates; however, you can increase this ratio if you want to define only a horizontal frame or you know that the height estimates are unreliable. The last two values set limits on the uncertainty in height allowed to have a site included and serve to remove from the stabilization poorly determined sites. For `stab_ite` the first value is the number of iterations used in the stabilization, the second the amount of reweighting that can take place between iterations, and the third the ratio of residual to uncertainty (sigma) allowed before a site is removed from the stabilization. You can change the last value to fine-tune the inclusion or exclusion of sites from the frame definition. These commands are discussed in more detail in the *glorg* help file and Section 3.2 of the *GLOBK Reference Manual*.

2.4 Using *sh_gamit* and *sh_glred*

Now that we've described the program flow and control files, we'll take you through a simple application of *sh_gamit* and *sh_glred* using the small network in southern California previously provided (prior to 10.7) in `gg/example`. The command for *sh_gamit* issued at the project-directory level (`/2000`) is

```
sh_gamit -expt scal -d 2000 034 035 036 -noftp -pres ELEV -copt x k p -dopt c ao >&! sh_gamit.log
```

In this example, we start with all of the data to be processed already present in the `/rinex` directory. If you wanted to add additional data available from a global or regional archive, you would specify the site names in `sites.defaults`, enter the ftp information (if not already present) into `gg/tables/ftp_info`, and remove the `-noftp` option from the call to *sh_gamit*. As a result of the command shown, *sh_gamit* will execute for each day the following steps, noted in the screen output redirected to `sh_gamit.log` :

- 1) Assign parameters for program flow, giving precedence first to the command-line arguments, then to the parameters set in `process.defaults` and `sites.defaults`, and then to default assignments within *sh_gamit* itself. In this case, the command-line entry `-noftp` overrides the default to search archives for requested or updated observation, navigation, and EOP files; and the command-line entries for which files to compress or delete at the end of the run override those set in `process.defaults`.
- 2) Create the day-directory and/or standard directories which do not yet exist (all of these are already present in the `gg/example` directory).
- 3) Link into the day directory (`/034`) the standard tables (see script *links.day*) and the RINEX files that contain data for the specified interval (00:00-24:00 as set in `process.defaults`).

- 4) Download orbital sp3 files from a global data center and create GAMIT g-files using script *sh_get_orbits*.
- 5) Run *sh_upd_stnfo*, which invokes program *mstinf* to update station.info from the RINEX headers. (It is recommended that this step be skipped by setting *xstinfo [expt]* all in *sites.defaults*.)
- 6) Run *makexp* to create the input files for *makex* (*scal.makex.batch*) and *fixdrv* (*dscal0.034*).
- 7) Run *sh_check_sess* to make sure that all of the satellites included in the RINEX observation files are present in the navigation file (*/brdc/brdc03400n*, previously downloaded at MIT from an IGS archive) and in the g-file (created previously at MIT from an IGS sp3 file).
- 8) Run *sh_makej* to create a j-file of satellite clock estimates from the sp3 file (default) or navigation file. .
- 9) Run *makex* to create x-files (observations) and k-files (receiver clock estimates) using phase and pseudorange data from the RINEX observation files, broadcast ephemeris from the navigation file, and satellite clocks from the j-file. A record of *makex*, showing the data found and any problematic data encountered is written to *scal.makex.infor*.
- 10) Run *fixdrv* to create the batch file for GAMIT processing. Though not used directly, *fixdrv* also reads the k-file of episodic clock values and fits a first-order polynomial to them as a crude check for jumps and rapid drifts in the receiver clock (*fixdrv.out*).
- 11) Execute the batch run to generate a tabular orbital ephemeris (*arc*), model the phase observations (*model*), edit the data (*autcln*), and estimate parameters (*solve*), a sequence completed twice in order that *autcln* may operate on flat residuals and that the final adjustments in *solve* are well within a linear range. A record of this run is not written to *sh_gamit.log* (to save space) but is recorded in *GAMIT.status*, *GAMIT.warning*, and *GAMIT.fatal* in the day directory.
- 12) Save the cleaning summary (*autcln.post.sum*) to *autcln.post.sum.scal* (potentially for archiving, though that's not done for this example) and write key information from *model* and *solve* to the HISTORY file, which, unlike all other files in the day directory, is appended rather than overwritten in reruns so that a record of previous runs is maintained.
- 13) Create sky plots of phase residuals and plots of phase vs elevation angle using the DPH files written by *autcln*; if the ImageMagic program *convert* program is available, translate the plots from postscript to png and move them into */figs*.
- 14) Invoke *sh_cleanup* to delete or compress files as specified by *-dopt* and *-copt*.

The most common problems with *sh_gamit* are missing or incorrect receiver and antenna information (“metadata”) in *station.info* and the loss of data due to bad tracking or bad coordinates.

There are two approaches you can take to providing metadata to GAMIT. If you have RINEX files for which you know all the headers are correct, you can have *sh_gamit* invoke *sh_upd_stnfo* to update *station.info* for each day using the header entries (no update

will be made if the `station.info` entry is present and matches the RINEX header). If the antenna height information is correct but the receiver and antenna names not IGS standard, you can still use this feature if you put into `/gg/tables/guess_rcvant.dat` a substring that will uniquely match what appears in the header. If you know that all of your receivers and/or antennas are of the same type, you can force their use by specifying them as `ant default` and `rcv default` in `guess_rcvant.dat`. If you expect `sh_gamit` to generate `station.info` entries from the RINEX header information, you should review the antenna and receiver names used in all of the headers before you start (e.g., by `grep`'ing on the RINEX files for 'REC #' and 'ANT #'). Antenna heights can also be problematic. In the RINEX standard, the header value is supposed to be a vertical height to antenna reference point (ARP), but often a slant height is actually given in the file. If the latter is the case, then `stinf_slthgt` in `process.defaults` can be set to a height above which the value will be assumed to a slant height to the outside edge of the ground plane. (Setting `stinf_slthgt` to 0 or a large number will cause all values to be interpreted as direct height measurements.)

If you have *any* doubts about the validity of the RINEX headers, it is better to create (and check!) `station.info` before you start the GAMIT processing. You can create a file with all of the entries for your survey by running `sh_upd_stnfo` manually with your RINEX files, then edit the file as appropriate. In creating this file, it is best to start with a template from the current MIT or SOPAC global `station.info` file (available in `/incremental_updates/tables`) so that you can conveniently add entries for continuous stations from the global file. This template can be header-only, but the preferred approach is to start with the full global `station.info` file and use the `-l [sitelist]` option of `sh_upd_stnfo` to extract only the stations you need, either from an existing list or one created automatically by `sh_upd_stnfo` from the sites with `ftprnx` in `sites.defaults` and/or the file names in your experiment `/rinex` directory. Hence, if you have a current copy of the MIT or SOPAC `station.info` in `gg/tables`, have run `sh_setup` to copy it into your experiment `/tables` directory, and have edited `sites.defaults` to specify the RINEX files you want from a remote archive (using `ftprnx`), you can run (in `/tables`)

```
sh_upd_stnfo -ref station.info -l sd
```

which will produce `station.info.new` with the global entries for only the `ftprnx` sites. (If the sites you need from the global `station.info` file are not in `sites.defaults` with `ftprnx`, but are present in the `/rinex` directory, you can use `-l sdrnx` or `-l rnx` in the `sh_upd_stnfo` command.) Then make sure the RINEX files in the experiment `/rinex` directory are not compressed, rename `station.info.new` to `station.info` and run (in `/tables`)

```
sh_upd_stnfo -files ../rinex/*o
```

`sh_upd_stnfo` also allows entries for `station.info` to be created from IGS log files or SINEX files. If you construct `station.info` in advance of your processing, set `xstinfo [expt] a11` in `sites.defaults` to block any attempt by `sh_gamit` to update the file from RINEX headers.

Bad a priori coordinates will result in `autcln`'s detecting too many cycle slips and deleting all of the data. A clear indication that this has happened is `Range rms` values greater than

about 20 m at the top of the `autcln.prefit.sum` file together with 0 for **DATA AMOUNTS** in the same file. When this happens, you should check the `[project]/tables/lfile` for the source of the coordinates used. If a priori coordinates for a station are not available in the L-file (or `apr` file) from previous processing, `sh_gamit` will by default invoke the `sh_rx2apr` script to perform a pseudorange solution. Coordinates good to 10-20 m can usually be obtained from the data at the station of interest (better if SA is off), but the preferred approach is to perform the solution differentially, using also a RINEX file from an IGS station with known coordinates. To make sure this happens, you should specify `ftprnx` in `sites.default` and have present in the `/rinex` directory or available via ftp from an IGS data archive the RINEX files for each day from one or more IGS stations. (You can use this setting to get a differential pseudorange solution even if you have `-noftp` specified for `sh_gamit` provided you copy the IGS data into the `/rinex` directory in advance of the run.) If a differential pseudorange solution was used and you still have bad coordinates, try executing `sh_rx2apr` manually with data from each of several days and compare the coordinates to see if the day you used originally was an anomaly because it was short or had bad pseudorange data. To by-pass `sh_rx2apr` and use the coordinates from the RINEX header, set `use_rxc = Y` in `process.defaults`. This option should be used only if you know that the header values are always present and accurate or if you have RINEX 3 files, which the programs `svpos` and `svdiff` invoked by `sh_rx2apr` will not yet support. Note that a large adjustment of coordinates, due to bad data or a short session, on one day can cause problems with the next day since `lfile` in the experiment `/tables` directory will be updated. You can avoid this update by copying into the `aprf` file specified in `process.defaults` any site coordinates that you know to be good; the L-file will be initialized with these values as processing begins for each day.

`sh_gamit` can also fail if it is unable to ftp required global RINEX files or orbital information from an IGS archive (CDDIS or SOPAC if not otherwise specified). The `GAMIT.fatal` message will usually make clear what file is missing. In this case, check the ftp connection manually and restart the processing.

For the most part, you can rerun a day after a failure with simply a remedy of the detected problem (e.g., a bad `station.info` entry). However, in some circumstances old corrupted files will be used: (a) Unless you specify `remakex Y` in the command line, any existing `x`-file in a directory will be used again and the script assumes that there is a valid `station.info` entry for this file (if not, the process will fail). (b) Any existing RINEX file linked in the day directory will be assumed to exist. If the link is now empty because you have renamed or removed the file in the remote directory, this may not be detected correctly on all systems. (c) A previously added `station.info` entry will be used (and not replaced) if it applies to the day being processed. (d) Coordinates in the L-file will be used if they exist (so if the entry has been corrupted it should be removed and/or correct coordinates put in to the `apr`-file).

Descriptions of how to run `sh_gamit` with sessions crossing day boundaries can be found in Section 6.3 of the GAMIT Reference Manual.

To generate time series from the GAMIT runs for the three days in the example, type at the project-directory level (/2000)

```
sh_glred -expt scal -s 2000 034 2000 036 -opt H G T >&! sh_glred.log
```

The script will execute the following steps, noted in the screen output redirected to `sh_glred.log` :

- 1) Search all day directories between /034 and /036 for GAMIT h-files containing the substring `scal` and run `htoglb` to convert these to binary h-files for `glred`. Since each GAMIT h-file contains two solutions, one with ambiguities estimated as real numbers (“biases free”) and one with ambiguities resolved (“biases fixed”), `htoglb` will create two binary h-files, with extents `glr` (GAMIT loose free) and `glx` (GAMIT loose fixed), respectively. They are stored in the `/glbf` directory and named with the year/month/day/hr/min, e.g `h0002031200_scal.glx` for day 034.
- 2) Generate in the `/gsoln` directory a `gdl` file (h-file list) for each day (`glx` is default).
- 3) Run `glred` for each day, using commands of the form

```
glred 6 globk_scat_00034.prt globk_scal_00034.log globk_scal_00034.gdl globk.cmd
```

The `.log` and `.org` files provide a record of the output.

- 4) Run `sh_plot_pos` to invoke program `tssum` to create PBO-format `.pos` files from the coordinates of each site on each day in the `.org` files and invoke GMT to plot the time series. (Specifying `E` instead of `T` on the command line will use the older program `ensum` to generate `mb_` files for plotting with `sh_plotcrd`.)

This task could be accomplished in individual steps by running `htoglb` directly with wild cards specifying the day directories, creating a `gdl` file in `/gsoln` using `'ls ../glbf/h*glx'`, running the program `glred` (rather than the script `sh_glred`) with this `gdl` file, and running `sh_plot_pos`. In fact, for velocity solutions and time-series using combined files, you will need to use this approach (see Chapter 4). The advantages of the script are threefold: 1) fewer commands, 2) it allows easy daily combination of local h-files with those from an external processing center (e.g. MIT or SOPAC), using the `LA`, `LB` and `LC` options (see Section 4.1 below); and 3) it allows easy aggregation of days into weekly or monthly combined h-files, using the `-ncomb` option (see the `sh_glred` help by typing the command without arguments). You can mix using `sh_glred` with running `glred` directly as long as you keep in mind two differences: 1) `sh_glred`, like `sh_gamit`, is launched from the project directory but executes `glred` within the `/gsoln` directory whereas `glred` is launched directly from within the `/gsoln` directory itself; and 2) `sh_glred` creates a `gdl`-file for each day whereas running `glred` itself efficiently requires creating a single `gdl`-file containing the h-files for all of the days. In a `gdl`-file, the `+` symbol is used to indicate to `glred` that h-files are to be combined before performing the solution. For example, using the file

```
../glbf/h1211021200_pan1.glx 1.0 +
../glbf/h1211021200_pan2.glx 1.0 +
../glbf/h1211021200_pcnw.glx 1.0 +
../glbf/nmt17125.e.glb 1.0
../glbf/h1211031200_pan1.glx 1.0 +
```

```

../glbf/h1211031200_pan2.glx 1.0 +
../glbf/h1211031200_pcnw.glx 1.0 +
../glbf/nmt17126.e.glb 1.0

```

glred would combine all four h-files for day 2012 11 2 before performing a solution, and then do the same thing for the four files for day 2012 11 3. (Running *globk*, rather than *glred*, would combine all of the files listed into a single solution whether or not the '+'s are present).

Other options of *sh_glred* specify the ftp'ing of data from a remote archive (F), removal of old h-files from the *gdf* directory (R), and compressing the h-files at the end of the run (C). Type *sh_glred* without arguments to see all options.

To avoid overwriting useful h-files or using obsolete ones, it is important to keep in mind the precedence rules of the script. For local data (*sh_gamit* day directories), specifying the H option will force *htoglb* to be rerun for all directories within the time span indicated, whether or not a binary file or link exists in the */glbf* directory. Omitting H will cause no new binary files to be created, so it is not possible to retranslate only a selected group of ascii H-files. This is not an important limitation, however, because *htoglb* runs quickly. For global ascii h-files ftp'd from SOPAC, setting H will also force *htoglb* to be rerun on any ascii H-files present or linked (by LA) in the H-file (*glbf*) directory, but you can safely set F since the script will not re-ftp any remote (ascii) H-files that are present.

Note that most of the shell scripts called by *sh_gamit* and *sh_glred* can be run stand-alone for specific processing tasks. The most useful of these are *sh_make_rinex* (templates for running *teqc* to translate raw data files), *sh_get_nav*, *sh_get_rinex*, *sh_get_orbits*, *sh_sp3fit*, *sh_update_eop*, *sh_link_rinex*, *sh_oneway* (to get sky plots from DPH files), and *sh_get_hfiles*. Type the name of the script without arguments to see the documentation.

3. Evaluating the Results of Daily Processing

There are three primary criteria you should use to determine if your phase processing produced a good result:

- All of the expected data were included.
- The data fit the model at the expected level.
- The uncertainties are acceptably small.

In most cases you can assess these three requirements quickly using the GAMIT summary emailed to you by *sh_gamit* (and saved as *sh_gamit_ddd.summary* in the day directory) together with the plots of daily repeatabilities created by *sh_glred*. Following is the summary file from day 034 of the southern California example:

```

Input options -expt scal -d 2000 034 -netext a -orbit IGSF -noftp -remakex Y
Processing 2000 034 GPS week 1047 4 Raw 0

```

```

/chandler/data30/rwk/active/example/034a
Disk Usage: 37537 Free 31764.5 Mbyte. Used 55%

Number of stations used 5 Total xfiles 5
Postfit RMS rms, total and by satellite
RMS IT Site All 01 02 03 04 05 06 07 08 09 10 11 13 14 15 16 17 18 19 21 22 23 24 25 26 27 29 30 31
RMS 26 ALL 4.4 46 35 56 42 38 42 42 38 51 44 61 41 0 42 44 40 40 42 36 52 40 40 38 49 38 37 45 55
Best and Worst two sites:
RMS 26 JPLM 3.2 3 3 4 3 3 3 3 3 4 3 3 3 0 3 3 3 3 3 3 4 3 3 3 4 3 3 4 4
RMS 26 MATH 3.5 4 2 5 4 4 3 4 4 4 4 4 3 0 3 3 3 3 3 3 4 3 3 3 4 3 3 3 4
RMS 26 7001 5.2 6 4 7 5 4 5 4 5 6 6 6 5 0 5 6 5 5 5 4 7 4 4 4 6 4 4 5 5
RMS 26 BLYT 5.5 6 4 7 5 5 5 6 5 6 5 7 5 0 6 6 5 5 5 4 6 5 5 4 6 4 5 5 7

Double difference statistics
Prefit nrms: 0.25309E+01 Postfit nrms: 0.19379E+00
Prefit nrms: 0.25241E+01 Postfit nrms: 0.20241E+00
Prefit nrms: 0.25309E+01 Postfit nrms: 0.18607E+00
Prefit nrms: 0.25241E+01 Postfit nrms: 0.18889E+00
Number of double differences: 15098

Phase ambiguities (Total WL-fixed NL-fixed: 100 96 88
Phase ambiguities WL fixed 96.0% NL fixed 88.0%

```

Check first that all of the data you expected got into the processing. The “Total xfiles” should equal the number of raw or RINEX files available. If the “Number of stations used” is less than the total x-files, then some x-files were created but then discarded because they were too small (tracking session too short or data discarded by *makex*) as measured against the `minxf` value you set in `process.defaults`, or because you have excluded them with the `xsite` option in `sites.defaults` or the `sh_gamit` command line.

There are three indications of data quality and they each measure slightly different things. The block of lines beginning with “RMS” are all extracted from `autcln.post.sum` and show the one-way root-mean-square residuals by satellite and station. In the RMS second line, the first value is an overall rms in mm. The remaining values on that line break down the scatter by satellite and report the value in tenths of mm to allow better discernment of differences that might indicate a bad orbital model for one satellite. The last four lines report the values for the two sites with the lowest (JPLM and MATH in the example) and the highest (7001 and BLYT) scatter. In a typical project, the best sites will have values of 3-5 mm, and the worst 7-9 mm. Values between 10 and 15 mm indicate high but acceptable levels of noise, but if you reweight the data using *autcln* (default and recommended) the uncertainties in position estimates for these sites will be 2-3 times higher than for the better sites. RMS values greater than 15 mm suggest a poorly tracking receiver, a high multipath environment, severe weather, or a problem with convergence in *autcln*, usually caused by poor coordinates or a short span of data. If the site’s coordinates had large adjustments from the preliminary run (e.g., because this was the first day of processing a new site) and the RMS value is high, try simply rerunning the day with the now-updated coordinates. For sites with high scatter, examining the sky plots and phase versus elevation plots in the `/gifs` directory may help you understand the source of the noise. If both of the “worst” sites have high rms, you should look at `autcln.post.sum` to check other sites, which might also have high values but did not make the “top two” in the summary.

If either or both of the “best” two sites have 0 RMS, then all of the data from these sites were removed by *autcln*. The most common reason was that *autcln* inserted too many “bias” flags (detection of a possible cycle slip), either because of poor a priori coordinates or poor receiver performance. The tables in *autcln.post.sum* allow you to determine the reason. If it is bad a priori coordinates, the pseudorange rms at the top of the file will make this immediately clear:

AUTCLN SUMMARY FILE: Version 3.22I

```

Clock and Range noise statistics at iteration 3
Site/PRN      Allan SD@100 #      Range rms      #
              sec (ppb)      (mm)
7001          1.552388      716            772.9      5353 ASH
BLYT          0.448878      2876           329.3      21905 ASH
JPLM          0.138763      2879           1101.2     19487 TRB
LNCO          38.975374      2877           1026.4     19982 TRM
MATH          100.000000     2876           482.8      18834 TRM

```

Maximum values of 1-2 m, as in the example, are typical; if the value is greater than 5 m, a bad site coordinate is likely the problem. You can corroborate your assessment using the table reporting what *autcln* did with bias flags:

BIAS FLAG REPORT: Types

```

ORG-Original JMP-Big Jump ION-Ion Jump GAP-Data Gap DDS-DD scan WLS-Wide Lane DDC-DD cleaning
SITE      # Flagged      |      # Remaining      |      # Edited      |
ORG JMP ION GAP DDS WLS DDC| ORG JMP ION GAP DDS WLS DDC| ORG JMP ION GAP DDS WLS DDC|
7001     0 0 17 21 1 0 0| 0 0 12 9 1 0 0| 0 0 5 12 0 0 0|
BLYT     0 0 3 27 3 0 0| 0 0 0 6 1 0 0| 0 0 3 16 2 0 0|
JPLM     0 0 32 266 16 0 0| 0 0 22 10 0 0 0| 0 0 10 222 11 0 0|
LNCO     0 1 26 61 2 0 0| 0 0 8 9 0 0 0| 0 1 18 28 2 0 0|
MATH     0 0 15 87 0 0 0| 0 0 14 10 0 0 0| 0 0 1 12 0 0 0|

```

The block labeled # **Flagged** reports how many bias flags were initially added scan for each station and the reason why--either gap or jump in the data. For example, the **DDS** column indicates the number added during the scanning of the double-difference residuals. If this number is high, *autcln* detected many discontinuities, which can be due to noisy phase data but would also result if there is a large slope in the residuals due to poor coordinates or orbits. The # **Remaining** block reports how many flags remained after *autcln* has finished its editing. You would like all stations to look like **BLYT**, but this is rarely the case. The # **Edited** block reports the number of bias flags removed by deleting the data affected by the bias flag (as opposed to removing the flag by reliably resolving the integer number of cycles between data segments). Confirmation of *autcln*'s action is given in the editing report:

EDITING REPORT AND SITE PARAMS

```

SITE      nCLN MnOUT SNR  LSNR GF03 RCLK GF02 BEND BCLS DDSC PFED GFUN BDL2 NODD ELEV EDIT MMRG ELCL  Good
      (deg) (deg) L1 L2
7001     10.0 10.0 0 0 0 0 0 0 0 74 40 0 17 0 0 12 7 0 0 0 5210
BLYT     10.0 10.0 0 0 0 0 0 0 104 239 26 0 2 0 0 1091 3512 0 0 0 20547
JPLM     10.0 10.0 0 0 0 0 0 0 9 59 677 0 26 0 0 677 8 0 0 0 18055
LNCO     10.0 10.0 0 0 0 0 0 0 0 274 404 0 5 0 0 430 2076 0 0 0 19148
MATH     10.0 10.0 0 0 0 0 0 0 0 14 44 0 8 0 0 0 0 0 0 0 18768

```

Note whether each site has the expected number of “good” data (the original sampling interval for 7001 in this example was 120s, compared with 30s for the other receivers, so the number of data is what we would expect). If a site shows many data deleted, the column headers tell you the reason; see the *autcln* help file and Section 4.2 of the *GAMIT Reference Manual* for an explanation of each header.

The last part of the *sh_gamit* summary file is extracted from the *solve* q-file. The first four lines list, respectively, the normalized rms (square root of χ^2 per degree of freedom) for the constrained solution with ambiguities free, constrained solution with ambiguities resolved, loose solution with ambiguities free, and loose solution with ambiguities resolved. With the current weighting of phase observations, all of these should be ~ 0.2 . If the constrained nrms values are significantly larger than the loose nrms, the data are good but the constraints you have imposed in the GAMIT solution, either on coordinates (*sittbl.*) or orbits (*sestbl.*), are too tight. If this is the case, try constraining only the most reliable site and look at the adjustments of the others in the q-file. The last line in the summary gives the percentage of wide-lane (WL) and narrow-lane (NL) ambiguities resolved. (Note: This form of the summary is for LC_AUTCLN; with LC_HELP there are only two numbers, the first being the total number of ambiguities estimated, WL + NL, corresponding to twice the first number in the LC_AUTCLN summary, and the second being the number of NL ambiguities resolved.) With LC_AUTCLN more than 90% of the WL ambiguities should normally be resolved for any size network unless you have short sessions, noisy pseudoranges, and/or you are not using a dcb.dat table that includes estimated values for the epoch of your data. The percentage of NL ambiguities resolved depends on the session length, size and configuration of the network, quality of the orbits and a priori coordinates, and atmospheric conditions. If it is less than $\sim 80\%$, there may be deficiencies you can address with a different analysis approach.

The definitive check of your data and processing is provided by the time-series generated by *sh_glred* as postscript files in */gsoln*. With 24-hr sessions and a robust stabilization, you should obtain uncertainties and repeatabilities at the level of 1-2 mm for horizontal coordinates and 3-5 mm for heights. With 8-hr sessions, the horizontal should be 2-4 mm and height 10-15 mm. If the uncertainties are high for some sites but not others, check the session length (RINEX or x-file), number of data deleted (editing summary of *autcln.post.sum*), and data noise (RMS table and “Elevation angle dependent RMS statistics of *autcln.post.sum* and/or “A priori receiver measurement error model” in the q-file). If the uncertainties for all sites are high, then check the record of the *glred* and *glorg* run, e.g. *globk_scal_00034.org*:

```

+++++
+ GLORG                      Version 5.11I +
+++++
Stabilization with 20.0% constant, 80.0% site dependent weighting.
Delete sites with 4.0-sigma condition.
Height variance factor      10.00 Position,      10.00 Velocity
For Position: Min dH sigma 0.0050 m;   Min RMS 0.0030 m,   Min dNE sigma 0.00050 m
For Velocity: Min dH sigma 0.0050 m/yr; Min RMS 0.0030 m/yr, Min dNE sigma 0.00010 m/yr
Sigma Ratio to allow use: Position   2.00 Velocity   2.00
=====
Starting Position stabilization iteration 1 L0002031200_scal.glx

```

For 5 sites in origin, min/max hgt sigma 451.3 452.8 mm; Median 452.2 mm, Tol 10.0 mm

Position system stabilization results

```
-----
X Translation (m)      0.24048 +-    0.00264 Iter  1 L0002031200_scal.glx
Y Translation (m)      0.29123 +-    0.00398 Iter  1 L0002031200_scal.glx
Z Translation (m)     -0.25412 +-    0.00330 Iter  1 L0002031200_scal.glx
Condition Sigmas used    0.0000    0.0000    0.0000
Sites and relative sigmas used in stabilization
BLYT_GPS  1.00  7001_GPS  1.00  MATH_GPS  1.00  JPLM_GPS  1.00  LNCO_GPS  1.00
For 15 Position Iter 1 Pre RMS  0.0908 m; Post RMS  0.00362 m L0002031200_scal.glx
For 5 sites in origin, min/max NE sigma 1.29 1.96 mm; Median 1.43 mm, Tol 1.00 mm
```

The top part of the file records the sites included in the stabilization. As *glorg* iterates the stabilization, it will remove sites that have large height uncertainties or horizontal and/or height residuals compared with the uncertainties. In the final iteration, there should be at least three (and preferable many more) sites left in the stabilization, and the ‘Post RMS’ should be at the level you expect for the uncertainties (1-5 mm). The next part of the file (not shown) echoes the *globk* and *glorg* command files (provided **CMDS** was set in *org_opt*); make sure these match what you intended. The next useful section is the position summary, which shows the adjustments and uncertainties of each of the sites in north, east, and up:

```
SUMMARY POSITION ESTIMATES FROM GLOBK Ver 5.11I
  Long.      Lat.      dE adj.  dN adj.  dE +-    dN +-    RHO      dH adj.  dH +-    SITE
  (deg)      (deg)      (mm)     (mm)     (mm)     (mm)
245.285     33.610     -3.78    2.72    1.59    1.37 -0.062   37.86    6.07 BLYT_GPS*
243.531     34.560      0.12   -0.37    1.02    0.98  0.039   -9.53    4.71 7001_GPS*
242.563     33.857      1.33   -0.64    0.86    0.83  0.012   -1.86    4.04 MATH_GPS*
241.827     34.205      0.50   -0.51    0.85    0.80  0.031   -4.66    3.87 JPLM_GPS*
240.942     36.360     -0.27    0.42    1.43    1.37 -0.103   -8.82    5.64 LNCO_GPS*
POS STATISTICS: For 5 RefSites WRMS ENU 1.36 1.01 14.27 mm NRMS ENU 1.30 1.02 3.07
```

The starred sites are those used in the stabilization (all in this case since the *apr*-file is based on a previous solution); if there is sufficient redundancy, the individual adjustments will be useful in determining if the quality (rms) of the stabilization is degraded by the inclusion of particular sites. The stabilization statistics at the end of the position summary are shown for each component (north east up) rather than a combination of the three as given in the output at the top of the file. A more detailed discussion of *globk* and *glorg* output can be found in Section 3.5 of the *GLOBK Reference Manual*.

4. Generating Time Series and Velocity Fields

When input to GLOBK as quasi-observations, h-files can be considered either individually (*glred*) to generate time series or as a group (*globk*) to estimate positions and velocities. In either case the most important decisions facing the analyst are how to edit and weight the data and how to define and realize the reference frame. In making these decisions, you need to consider what stations to include explicitly, how to treat the orbits and earth orientation parameters (EOP), and practical constraints on computation speed

and data storage. In this chapter we discuss strategies you might use to achieve your analysis objectives with the tools available in the GLOBK suite of programs. The computation of multi-year solutions may be carried out conveniently in a directory (e.g. /vsoln) parallel to the directories used for each survey or year of continuous data. At this same level, you may want to create an additional /tables directory containing files common to all the years and the velocity solutions. If you carry out a series of multi-year analyses, then command files in additional processing directories (/asoln, /bsoln, ..) can use the same path (./tables) to these common files.

4.1 Combining h-files

There are several reasons why you may want to combine the h-files from your daily GAMIT processing with other h-files before generating a times series or velocity solution. you have more than ~50 sites in a regional network, it is more efficient and just as accurate to process these in GAMIT networks of 30-50 sites and then combine them in GLOBK than to use a single large network (the GAMIT limit is 99 sites). Further, if you are processing a regional network and want to tie it rigorously to a larger regional or global reference frame, you can do so by combining your h-file(s) with those generated by MIT or SOPAC from their IGS processing or another analysis center's processing of regional continuous networks. Finally, to obtain more useful long-term statistics from your time series, to strengthen the reference frame for survey-mode observations, or to reduce the computational time for velocity solutions, you may wish to first combine the h-files from 5-30 days into a single h-file to be used in subsequent solutions. We discuss the pros and cons of these strategies in Sections 4.3 and 4.4, but their mechanical implementation is straightforward. For processing of a single day, *sh_glred* combines the GAMIT processing from multiple GNSS or multiple subnets using the `-netext` option and includes independently processed regional or global networks using the LA, LB or LC options. Running *sh_glred* for a single day with `-globk_predit COMB` specified will direct *globk* to save a combined h-file for further processing. For multiple days, this option together with `-ncomb` will aggregate the data over several days.

sh_glred allows you to automatically download and/or link in h-files from an external source. If the F option is specified, h-files implied by the `-net` option will be downloaded from MIT or SOPAC into the primary h-file directory (specified by `glfpath` in `process.defaults` and nominally /glbf). Alternatively, you can collect the h-files in advance in the directory specified by `hfn` in `process.defaults` and then set the LA, LB, and/or LC options to link these files into /glbf. LA refers to ascii h-files (requiring *htoglb* translation) of the form `h[net][expt]?.yyddd` (e.g. SOPAC network files), LB to binary h-files of the form `hyyddmm????_[net][expt].gl?` (with `glx` given precedence over `glr`), and LC to binary h-files of the form `Hyyddmdd_[net][expt].GLX` (e.g., MIT combined h-files). For example, to use local processing in combination with MIT global h-files previously downloaded onto your system, the command to generate a 30-day time series for experiment 'emed' would be

```
sh_glred -expt emed -s 2009 121 2009 150 -net MIT -opt H LC G T
```

Since *sh_glred* will look for all binary h-files in the */glbf* directory, created previously when you generated the time series, you can leave out the *-net*, *H*, and *LA* options when combining the files. This feature is particularly useful if the days you want to aggregate are not continuous (e.g. from a survey) and you have used the *-local* option in the *sh_glred* command that generated the time series.

If you are combining data over a span that is long enough that the error in the a priori velocity of any of your sites is large enough to cause an error in position, you should estimate velocities in the combination; however, it's generally better to make the span of the combination short enough that this is not an issue.

4.2 Data editing

Your solutions will be corrupted if you include data that are statistical outliers. For a time series from independent h-files, an error in one component of one site's coordinates will not affect any other site (and may have minimal effect on the other components), but as soon as you combine h-files with common parameters, whether multiple networks on a single day or the results from more than one day, the different estimates of the common parameter will clash, raising chi-square and distorting the solution. There are two ways you can remove outliers: using the *rename* command of the *eq_file* and using the *sig_neu* command directly in the *globk* command file. In the *rename* command, if you designate the extent as *_xcl* the site will always be excluded; with *_xps* the site will be excluded from any solution of more than one day but will still appear in daily time series; e.g.

```
rename MIT algo_gps algo_xcl 1997 5 14 0 0 1997 5 17 24 0
```

will remove from the solution the observations of ALGO in any h-files containing the characters "MIT" between 14 and 17 May 1997. Note that the date span specified must completely encompass the start time of the first h-file and the end time of the last h-file. The h-file selector entry and/or the dates may be omitted for a more expansive exclusion. With the *sig_neu* command you can effectively remove the effect of an error in a particular component by adding sufficient noise that it has negligible weight, e.g.

```
sig_neu MIT algo_gps 0 0 .5 1997 5 14 0 0 1997 5 18 0 0
```

would reduce the effect of an error in height by adding 0.25 m^2 in quadrature to the variance of the height component as estimated from the h-files specified.

Which of these approaches you choose is a matter of taste and could depend on the tools you use for editing. For continuous data, when you can afford to remove many outliers without weakening the solution, using the *nsigma* option of the *tsfit* program (see Chapter 4 of the *GLOBK Reference Manual*) to automatically generate XPS commands, or the and the MATLAB-based interactive program *tsview* (<http://www-gpsg.mit.edu/~tah/GGMatlab>) to generate XPS commands with the click of a mouse, are quite convenient. For survey-mode data, when every observation counts and you often

want to down-weight heights but not horizontal components or only one horizontal component, `sig_neu` commands are more convenient. The GAMIT utility `grw` can be used to generate `sig_neu` commands with only a few key-strokes.

4.3 *Weighting the data for realistic uncertainties*

As noted in Section 1.2, the dominant errors in GPS observations are not random, but rather have correlation times ranging from a few minutes (multipath, water vapor) to days or months (station motions due to monument instability and atmospheric, hydrological, and ocean loading; non-gravitational forces on the satellites). Ignoring these correlations will result in uncertainties that are too optimistic, mildly so for observations of a few days, more strongly so for continuous data. In this section we assume that you understand the theoretical and empirical basis for various approaches, and we describe how to implement them in GLOBK. (For some theoretical background see the “Error Analysis” presentation from a recent workshop on the Documentation of the GAMIT/GLOBK web site.)

Studies of long-term GPS coordinate time series have shown that the noise over periods of a few days is nearly white but increases steadily for longer periods. With continuous data we can analyze the time series and, based on the character of the noise over periods of weeks to years, infer the noise at the long periods relevant to estimating the error in site velocities or long-term decay following an earthquake. A Kalman filter such as `globk` cannot without significant complication realize all possible error models (in particular a “flicker noise” model that best fits most GPS time series), but it can easily realize the two “end-member” models—white noise and a random walk—that together allow us to achieve meaningful short-term statistics for data editing and realistic uncertainties for estimated velocities.

The χ^2 (chi-square) increments (`chii`) computed by `globk` when h-files are combined reflect the inconsistency in the coordinate estimates from the current solution and the estimates from the new h-file and can usually be seen in the time series. If the data from all sites are properly weighted for their short-term scatter, the nrms of the time series and the chi-square increments should be ~ 1.0 . Chi-square increments less than one will occur when there is little redundancy or if you have down-weighted the data to allow for more realistic velocity estimates. Values greater than one will occur if the sigmas on the h-files are too small or there are uncompensated outliers among the coordinate estimates. ***These must be found using the time series and corrected as described in Section 4.2.***

We have noted earlier that the weighting of the phase data in GAMIT is such that the coordinate uncertainties in daily h-files are mildly pessimistic compared to the daily scatter, so you should expect chi-square values of 0.3 to 1.0 when you stack these files in `globk`. If you combine many days together, however, the h-file uncertainties will get smaller, by the square root of the number of days combined, and the chi-square values increase linearly with the number of days. You can compensate for this by adding white noise to the coordinate estimates using the `sig_neu` command. The values to be added can be determined from the short-term scatter in the time series. Adding white noise for

a uniform network of continuous stations is, strictly speaking, not necessary since the true uncertainty in velocity estimates will be dominated by the long-period noise added using `mar_neu` (random-walk) command, but it can be useful in editing by establishing a more realistic ratio between the uncertainties within an h-file that has a combination of continuous and survey-mode data. For example, if some position estimates in the h-file are based on thirty 24-hr sessions and others on two 24-hr sessions, the position uncertainties on the h-file for the 30-day sites will be a factor of four smaller than the 2-day sites even though their true uncertainties are nearly the same because of the dominance of correlated noise. To take an example, suppose the formal uncertainty and scatter in horizontal coordinates for all sites from a 24-hr session is 1.0 mm. In the combined h-file, the uncertainty for the 30-day site will be 0.2 mm and for the 2-day site 0.7 mm. If we add quadratically 0.75 mm of white noise to the horizontal coordinates of all sites on the h-files (`sig_neu all .00075 .00075 0`), then the uncertainties used in the solution will become 0.8 mm for the 30-day sites and 1.0 mm for the 2-day site, more closely reflecting their scatter (and hence contribution to χ^2). You may also want to add white noise for individual stations that show a higher level of short-term scatter than is reflected in their uncertainties---that is a higher nrms in the daily time series. Use of the `sig_neu` command for reweighting is preferred over the variance factor used with h-files in the gdl list since an elevated noise level is usually associated with only a subset of sites in the h-file. An exception would be when you have h-files generated from GAMIT solutions using different sampling times, in which case the variance factor is useful to balance the weight with other h-files in your solution.

The primary way we account for the long-period noise that most influences velocity estimates is by adding a random walk to the error model used by `globk`. For sites with ~100 or more position estimates, the appropriate value of the random walk for each component can be determined using the First Order Gauss-Markov Extrapolation (FOGMEX) or “realistic sigma” algorithm described by *Herring* [2003] and in the ‘Error Analysis’ presentations from the workshops. The algorithm uses the scatter in the time series for all possible averaging times (e.g. 1 day to 600 days for a 1200-day time series) to determine how the time series statistics depart from white noise. If the noise is white, the rms should decrease as the square root of the averaging time, and the nrms stay the same. In practice, however for GPS time series, the rms decreases much more slowly with averaging time, and nrms increases (since the formal uncertainty decreases). By fitting nrms (actually χ^2) versus averaging time to an exponential function (expected for a first-order Gauss-Markov process) and evaluating this function for infinite averaging time, the algorithm determines both the scale factor to be applied to the white-noise velocity sigma to get a more realistic sigma and the value of the random walk that will produce this sigma in the `globk` solution. To get the `mar_neu` commands, run

```
sh_gen_stats -ts SUM.tsfit
```

where SUM.tsfit is the output of an `sh_plot_pos` run invoking `tsfit`, (or `tsfit` directly); or

```
sh_gen_stats -ir va[root].ens
```

where *[root]* is an identifier of your choosing and the input file has the name *va[root].ens*, obtained by renaming the VAL file from running *sh_plotcrd* (or *ensum* or *enfit* directly). You can also invoke the FOGMEX algorithm from within *tsview* by selecting Realistic Sigma. For sites with fewer than ~100 estimates, the values you use for the random walk will necessarily be less precise, so you might use, for example, the median value from *sh_gen_stats* for the network or an “eyeball” estimate of long-period systematics in the time series.

4.4 Realizing a reference frame

Although the GPS satellites provide a natural dynamic frame for ground-based geodesy, the doubly differenced phase observations (or equivalently, undifferenced phase with clocks estimated or provided) do not tie a ground station to the orbital constellation at the millimeter level we require for scientific studies. Rather, we define and realize a precise terrestrial frame by applying constraints to one or more sites in our network. GLOBK allows two approaches. The simplest, used also in GAMIT, is to apply in the *globk* command file tight a priori uncertainties on the coordinates (positions and velocities) of one or more sites, e.g.

```
apr_neu all 1 1 1 .1 .1 .1
apr_neu algo .001 .001 .003 .001 .001 .003
apr_neu drao .002 .002 .002 .003 .003 .010
```

This “finite constraints” approach is rarely used in GLOBK, however, because it can distort the network if the assigned constraints are not correct for the a priori coordinates and data in your solution.

A more rigorous approach to frame realization is through “generalized constraints”, in which you minimize the adjustments of coordinates of the frame-defining sites while estimating translation, rotation, and sometimes scale (Helmert parameters). With this approach, all of the reference sites are free to adjust (hence revealing bad data or coordinates) and any frame realized with a particular set of reference sites will differ from a frame realized with another set only in translation, rotation (and scale), with no internal distortion. You enact this approach by keeping the constraint in *globk* free

```
apr_neu all 1 1 1 .1 .1 .1
# EOP loose if estimating rotation in glorg
apr_wob 10 10 10 10
apr_ut1 10 10
mar_wob 3650 3650 365 365
mar_ut1 365 365
# EOP tight if estimating only translation in glorg
x apr_wob .25 .25 .1 .1
x apr_ut1 .25 .1
```

and invoking *glorg* to apply generalized constraints (“stabilization” in GLOBK jargon)

```

pos_org xtran ytran ztran xrot yrot zrot
rate_org xtran ytran ztran xrot yrot zrot
# translation-only
x pos_org xtran ytran ztran
x rate_org xtran ytran ztran

```

Estimating both translation and rotation in *glorg* is necessary for global and large regional networks and preferred for any network over ~50 km in extent. (The scale parameter can usually be omitted—but see the discussion in *Dong et al.* [1998].) However, estimating rotation in addition to translation is robust only if you have at least six stabilization sites with a good geometric distribution. If there is only one site at the outer edge of the network (i.e. with a long “lever arm”), all of its error will go into the combination of rotation parameters in its direction. When this happens, both the uncertainty and residual of that site will be very small, there will be insufficient redundancy to provide stability to the network, and the stabilization statistics will be less meaningful. When you estimate translation only, you can get by with fewer stabilization sites and the geometry is much less important.

The simplest and most robust approach to frame realization, for all but the smallest networks, is to incorporate into your solution 10 or more sites whose coordinates are included with small uncertainties in the apr-file from the most recent International Terrestrial Reference Frame (ITRF) or its current IGS realization. The GLOBK template command files are set up to use *igs15_comb.apr*, which is the current IGS 2014 realization plus the addition of older, no longer used sites from *itrf14.apr*. The *igs14_comb.eq* file that accompanies this apr file has rename commands that are consistent with the 8-character site names in *igs14_comb.apr* (or *itrf14.apr*). In your solutions you can realize this frame either by including data from all of the chosen reference sites in your GAMIT processing, run in BASELINE mode with IGS orbits fixed, or by including in your GAMIT processing 3-4 IGS sites (not necessarily reference sites) that will tie your h-file to an h-file generated by MIT or SOPAC from global processing. To be completely rigorous in this latter case, you should include orbit estimation in your GAMIT run (RELAX mode) and allow the global h-file to determine the orbit. However, in practice with current IGS orbits, you can keep them fixed in the regional solution (BASELINE mode in GAMIT) and allow them to adjust implicitly (in the global solution) by omitting the *apr_svs* command in *globk*. Whether orbits are estimated implicitly or explicitly for the global network, you need to include a fully global h-file (e.g. MIT GLX or all of the SOPAC igs h-files), though you do not have to explicitly estimate the coordinates of all the sites. The principle here is that the global h-file(s) includes all of the information from processing the phase data whether or not the parameters (orbital or site coordinates) are explicitly estimated. Thus you can explicitly estimate (*use_site*) only the sites you intend to use in *glorg* for stabilization or tectonic frame realization (*plate* command of *glorg*) or which are otherwise important scientifically for your study, thus saving considerable computation time compared with estimating explicitly the orbits and the coordinates of 300+ sites in the global h-files. Using externally generated

GLOBK h-files gives you access to a large number of stations without the computational burden of running GAMIT yourself with a large network. The potential disadvantage is that the models you have used may not match those used by the external processing center (some matter more than others) and there is some burden imposed in downloading and storing the files (15-20 Mb per day) on your system. The script *sh_get_hfiles*, invoked directly or via *sh_glred* facilitates downloading the files.

If you have a small network with only one or two (or perhaps no) sites with good a priori coordinates, you may be able to realize an adequate reference frame by fixing or tightly constraining one site. This works because the uncertainties and errors in “absolute” coordinates (relative to the satellites) map into uncertainties and errors in relative coordinates (your primary interest) roughly reduced by a factor of the satellite altitude (20,000 km) to the baseline length. So, for example., a 1-m uncertainty (or error) in the coordinates of a constrained site induces an uncertainty (or error) of only ~ 1 mm over a 20-km baseline. (The actual reduction depends on session length and geometry, but for short baselines you have considerable latitude in setting the a priori constraint.) Although you can apply the constraints with the *apr_neu* command in *globk*, as noted above, you may want to invoke *glorg* for other reasons and prefer to leave the *globk* constraints loose and apply the constraint using the *force* or *constrain* commands:

```
constrain algo npos 0. .001
constrain algo epos 0. .001
constrain algo upos 0. .003
constrain algo ndot 0. .001
constrain algo edot 0. .001
constrain algo udot 0. .003
```

When generating time series and velocity solutions used to evaluate the quality of the data and your analysis approach, the theoretical definition of the reference frame is not important. It is usually best to carry out these steps in the no-net-rotation (NNR) frame of the ITRF (and strictly speaking, you should use this frame if you are not estimating orbits since it is consistent with the EOPs). Eventually, however, you will want to view the velocities in a frame that is natural for geophysical interpretation, and that is usually with respect to a stable tectonic block near your network. If you want to use the realization of a major plate as determined from the ITRF data set (e.g. *Altamimi et al.* [2012]), then it is easy to do so simply by substituting in *glorg* (not necessarily in *globk*) one of the rotated ITRF *apr* files provided in *gg/tables* (e.g. *itrf14_aura.apr*). The quality of the stabilization should be identical to one carried out with *igs14.apr* (NNR) since the relative motions of the sites has not been changed. If you want to realize a plate or smaller rigid block from your own solution, then you can do so using the *plate* command of *glorg*, e.g.

```
plate noam algo nlib piel rcm5 brmu chur
```

With this command present, *glorg* will estimate the rotation vector (Euler pole) for a block (spherical cap) containing these sites with respect to the stabilization frame. The

org-file print will contain the components and uncertainties of the rotation vector and will replace the velocity adjustments from the stabilization (i.e., with respect to the apr-file) with residuals with respect to the plate prescribed to include that site (the velocity estimates themselves remain in the frame of the apr-file). You can estimate any number of plates in a single solution so long as they are nearly independent and no one of them contains almost all of the sites used for stabilization (this will create a numerical instability). Running the script *sh_org2vel* with the *glorg* print file as input and the plate(s) specified with the names used in the plate command will produce velocity summary file(s) with the motions of *all* sites in the solution with respect to each of the plates.

4.5 Generating time series and velocity solutions

To generate time series or estimate velocities from several years of data, you need to run *glred* or *globk* directly rather than using *sh_glred*. As with creating irregular combined h-files, you can create the gdl file using the 'ls' command from the directory you intend to use for the multi-year analysis. For example, for a multiyear analysis in pnw/vsoln using combined h-files from individual years,

```
ls ../pnw??/gsoln/*GLX > pnw_all.gdl
```

or, if you have not aggregated the data,

```
cat ../pnw??/gsoln/*.gdl > pnw_all.gdl
```

using cat with the gdl files produced by *sh_glred*, rather than ls with the glx and GLX files in /glbf avoids having to add the + signs for multiple files within a day when running *glred* for the long-term times series. (When running *globk* to get velocities all files are combined regardless of whether the + signs are present or not.)

Your first step should always be to generate time series so that you can evaluate the statistics of your data and determine if there are any outliers that will distort the velocity solution. To run *glred* directly to produce a time series from this file, set (uncomment e.g.

```
glred 6 glred.prt glred.log pnw_all.gdl globk.cmd >&! glred_rep.out
```

The solutions for all h-files, obtained independently, are written into a single print file (specified by *prt_opt* for finite constraints using *globk*, *org_opt* for generalized constraints using *glorg*) so you can plot the results with

```
sh_plot_pos -f glred*.org -r -t NONE
```

(Alternatively you can create/save residual pos files for inspection and repeated plotting by running *tssum* first and then *sh_plot_pos* with *.pos instead of *.org for the input files.) The first check of the solution for each epoch is the quality of the stabilization. You can

get a summary of the statistics by `grep`'ing on `'POS STAT'` in the print file. The NRMS values for the stabilization should be near unity in all three components, and the WRMS 1-2 mm in horizontal and 3-10 mm in vertical (potentially higher if vertical was down-weighted more than the default factor of 10). Check to make sure that no epoch has too few sites in the stabilization. If you find any problems, look at the solution itself for that epoch, noting which sites were removed from the stabilization and/or have large adjustments in the position summary. Next look at the histograms of `nrms` and `wrms` generated by `sh_plot_pos` to see if the distribution of scatters among your sites is approximately Gaussian with the median `nrms` ~ 1.0 . Finally, unless you have a network of hundreds of sites (in which case you are probably too experienced to need this chapter), you should view the time series for every site to be included in your solution, whether or not it is of direct scientific interest. Look for outliers at individual epochs and sites with unusually high `nrms` (> 1.5 - 2.0 , depending on how you have weighted the data). If a large number of sites have outliers at a single epoch, review the GAMIT processing and the stabilization. Once you have identified any problematic position estimates and created `rename` or `sig_neu` commands to remove them, you should repeat the time series to verify that your entries accomplished what you intended.

Once you are satisfied with your time series, you can run `globk` with the same `gdl`-file to obtain a velocity estimate:

```
globk 6 globk.prt globk.log.pnw_all.gdl globk..cmd VEL >&! glred_vel.out
```

where the `VEL` option invoked with the template `globk.cmd` file will turn on velocity estimates and printout:

```
apr_neu  all  10 10 10 1 1 1
org_opt  PSUM VSUM GDLF CMDS
```

and `glorg.cmd`, invoked from within `globk_vel.cmd` includes stabilization for velocity as well as position:

```
* Set parameters to estimate in stabilization
  pos_org  xtran ytran ztran xrot yrot zrot
  rate_org xtran ytran ztran xrot yrot zrot
```

The `org`-file output will contain stabilization information and a summary table for velocities as well as positions. Also, the experiment list will now contain all of the files used and the computed chi-square increments as each successive `h`-file is added to the solution:

EXPERIMENT LIST from vel.srt

#	Name	SCALE	Diag	PPM	Forw Chi2	Back Chi2	Status
1	H950820_PNW.GLX	1.000	0.000		0.115	-1.000	USED
2	H970607_PNW.GLX	1.000	0.000		0.220	-1.000	USED
3	H980813_PNW.GLX	1.000	0.000		0.234	-1.000	USED
5	H990516_PNW.GLX	1.000	0.000		0.184	-1.000	USED

```
6 H010719_PNW.GLX      1.000   0.000   0.295  -1.000  USED
```

With a weighting of the coordinates estimates such that the uncertainties from each (combined) h-file are ~1 mm horizontal and ~5 mm vertical, the chi-square increments are typically less than 0.5 for regional data alone and 0.4 to 1.0 for global data. If an h-file is based on a poor GAMIT solution or there is a model incompatibility with previous h-files, the chi-square increment will be anomalous. When this occurs, you will need to return to the time series to see which sites show outliers that would create an incompatibility. A common example is a wrong antenna height for a station, which will show up as a height anomaly in the time series. How much chi-square is increased by a problem at one site will depend both on the size of the error and how many sites are in the solution. Very high chi-square values can result if you have two sites in the solution with the same name but at different locations. To guard against this problem, you should run *glist* before you start the processing (see Section 5.1 of the *GLOBK Reference Manual*).

To plot the velocities, use

```
sh_plotvel -f globk_vel.org -R244.5/251/40.5/46.5
```

where the `-f` argument is the `prt`, `org`, or `vel` file from which the **SUMMARY VELOCITY** is to be plotted, and the second command-line entry gives the longitude and latitude range for the plot using standard GMT commands. See the documentation at the top of the script (or type `sh_plotvel -help`) for additional options for displaying site names, scaling the uncertainties, setting the confidence level for error ellipses, and adding topography, fault maps, and other geographic features. The scripts *sh_map_calif*, *sh_map_china*, and *sh_map_elements* in `gg/com` may be helpful as templates.

For large networks, particularly those including continuous stations with discontinuities and non-linear motion due to earthquakes, the interactive Matlab-based programs *tsview* and *velview* can be powerful tools. Their use and installation are documented on the GAMIT/GLOBK webpage (<http://www-gpsg.mit.edu/~tah/GGMatlab>). As a further aid to handling large data sets, we have recently developed programs (*tssum*, *tsfit*) that allow “prototyping” of GLOBK solutions by manipulating time series to identify discontinuities and non-linear effects quickly (see Chapter 4 of the *GLOBK Reference Manual*).

It will often be the case that the set of stations you use for stabilization of the time series for editing purposes define a reference frame that is inherently weaker in your region of interest than the final velocity solution--either because the editing frame encompasses a larger region and hence is more affected by spatially correlated errors, or because the number of well-known stations available for stabilization of individual h-files is much less than the total number of stations in the solution. The time series that best represents your final velocity solution is one that is stabilized with all of the stations in the solution. Thus, after you obtain this solution, you should rerun *glred* with an enlarged `stab_site` list and an `apr`-file generated from the velocity solution. To get the `apr`-file, use *sh_exglk*,

and to generate a `stab_site` list to include all sites with position and velocity uncertainties below a specified level program `org2stab`.

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