

# GNU Gama 1.11

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Adjustment of geodetic networks  
Edition 1.11 (16 August 2011)

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# Table of Contents

<b>1</b>	<b>Introduction</b>	<b>1</b>
1.1	Download	2
1.2	Install	2
1.3	Program <code>gama-local</code>	2
1.3.1	Reductions of horizontal and zenith angles	4
1.4	Contributors	5
1.5	Reporting bugs	5
<b>2</b>	<b>XML input data format for <code>gama-local</code></b>	<b>7</b>
2.1	Angular units	7
2.2	Prolog	7
2.3	Tags <code>&lt;gama-local&gt;</code> and <code>&lt;network&gt;</code>	8
2.4	Network description	9
2.5	Network parameters	9
2.6	Points and observations	9
2.7	Points	10
2.8	Set of observations	11
2.9	Directions	12
2.10	Horizontal distances	13
2.11	Angles	13
2.12	Slope distances	14
2.13	Zenith angles	14
2.14	Height differences	15
2.15	Control coordinates	16
2.16	Coordinate differences (vectors)	16
2.17	Example of local geodetic network	17
<b>3</b>	<b>Network adjustment with <code>gama-local</code></b>	<b>21</b>
3.1	Approximate coordinates	22
3.2	Gross absolute terms	23
3.3	Parameters of statistical analysis	24
3.4	Test on the reference standard deviation	25
3.5	Information on points	26
3.6	Adjusted observations and residuals	29
3.6.1	Test on normal distribution of homogenized residuals	30
3.7	Identification of weak network elements	30
3.8	Estimation of real errors	31
3.9	Test on linearization	32

<b>4</b>	<b>Data structures and algorithms .....</b>	<b>35</b>
4.1	Observation data and points .....	35
4.2	Supported ellipsoids .....	37
4.3	Transformation from spatial to geographical coordinates .....	39
4.4	Class <code>g3::Model</code> .....	40
<b>Appendix A</b>	<b>Copying This Manual .....</b>	<b>43</b>
A.1	GNU Free Documentation License .....	43
A.1.1	ADDENDUM: How to use this License for your documents .....	49
<b>Concept Index</b>	<b>.....</b>	<b>51</b>

# 1 Introduction

GNU Gama is a project dedicated to adjustment of geodetic networks. It is intended for use with traditional geodetic surveyings which are still used and needed in special measurements (e.g., underground or high precision engineering measurements) where the Global Positioning System (GPS) cannot be used.

In general, surveying is the technique and science of accurately determining the terrestrial or three-dimensional spatial position of points and the distances and angles between them.<sup>1</sup>

Adjustment is a technical term traditionally used by geodesists and surveyors which simply means “application of the least squares method to process the over-determined system of measurements” (statistical methods other than least squares are used sometimes but are not common). In other words, we have more observations than needed and we are trying to get the best estimate for adjusted observations and/or coordinates.

*Adjustment of geodetic networks* means that we have a set of points with given coordinates coordinates of some points and a set of observations among them. What is typical of adjustment of special geodetic measurements is that the resulting linearised system might be singular (we can have a network with no fixed points) and we are not only interested in the values of ‘adjusted parameters and observations’ but also in the estimates of their covariances. This is what Gama does.

Gama was originally inspired by Fortran system Geodet/PC (1990) designed by Frantisek Charamza. The GNU Gama project started at the department of mapping and cartography, faculty of Civil Engineering, Czech Technical University in Prague (CTU) about 1998 and its name is an acronym for *geodesy and mapping*. It was presented to a wider public for the first time at FIG Working Week 2000 in Prague and then at FIG Workshop and Seminar at HUT Helsinki in 2001.

The GNU Gama home page is

<http://www.gnu.org/software/gama/>

and the project is hosted on

<http://savannah.gnu.org/cvs/?group=gama>

GNU Gama is released under the GNU General Public Licence and is based on a C++ library of geodetic classes and functions and a small C++ template matrix library `matvec`. For parsing XML documents GNU Gama calls the `expat` parser version 1.1, written by James Clark. The `expat` parser is not part of the GNU Gama project, and is simply used by GNU Gama.

Adjustment in local Cartesian coordinate systems is fully supported by a command-line program `gama-local` that adjusts geodetic (free) networks of observed distances, directions, angles, height differences, 3D vectors and observed coordinates (coordinates with given variance-covariance matrix). Adjustment in global coordinate systems is supported only partly as a `gama-g3` program.

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<sup>1</sup> Wikipedia, <http://en.wikipedia.org/wiki/Surveying>

## 1.1 Download

GNU Gama can be found in the subdirectory `/gnu/gama/` on your favourite [GNU mirror](#) or checked-out from the GIT. See our project page at [savannah](#) for more information.

To get an anonymous read-only access to the GIT repository for the latest GNU Gama source, issue the following command

```
git clone git://git.sv.gnu.org/gama.git
```

The collection of sample networks is available separately. To checkout the `gama-local` examples from GIT use the command

```
git clone git://git.sv.gnu.org/gama/examples.git
```

## 1.2 Install

GNU Gama is developed and tested under Debian GNU/Linux (<http://www.debian.org/>). A static library `libgama.lib` and executables are build in folders `lib` and `bin`. You can compile Gama easily yourself if you download the sources. If `expat` XML parser is installed on your system, change to the directory of Gama project and issue the following commands at the shell prompt

```
$ ./configure
$ make
```

If the script `configure` is not available (which is the case when you download source codes from a git server), you have to generate it using auxiliary script `autogen.sh`. To compile and build all binaries. Run

```
$ ./configure [--bindir=DIR --infodir=DIR]
$ make install
```

if you want also to install the binaries. You can use `configure` parameters if you need to change directories where user executables and info dosumentation should be installed.

## 1.3 Program gama-local

Program `gama-local` is a simple command line tool for adjustment of geodetic *free networks*. It is available for GNU Linux (the main platform on which project GNU Gama is being developed) or for MS Windows (tested with Borland compiler from Borland free command line tools and with Microsoft Visual C++ compiler; support for Windows platform is currently limited to maintaing compatibility with the two mentioned compilers).

Program `gama-local` reads input data in XML format ([Chapter 2 \[XML input data format for gama-local\], page 7](#)) and prints adjustment results into ASCII text file. If output file name is not given, input file name with extension `.txt` is used. If development files for Sqlite3 (package `libsqlite3-dev`) are installed during the build, `gama-local` also supports reading adjustment input datata from an sqlite3 database. If run without arguments `gama-local` prints a short help

```
$ ./gama-local
```

```
Adjustment of local geodetic network          version: 1.11 / GNU g++
*****
```

<http://www.gnu.org/software/gama/>

```
Usage: gama-local input.xml [options]
       gama-local input.xml --sqllitedb sqlite.db --configuration name [options]
       gama-local --sqllitedb sqlite.db --configuration name [options]
       gama-local --sqllitedb sqlite.db --readonly-configuration name [options]
```

Options:

```
--algorithm  svd | gso | cholesky | envelope
--language   en | ca | cz | du | es | fi | fr | hu | ru | ua
--encoding   utf-8 | iso-8859-2 | iso-8859-2-flat | cp-1250 | cp-1251
--angles     400 | 360
--latitude   <latitude>
--ellipsoid  <ellipsoid name>
--text       adjustment_results.txt
--xml        adjustment_results.xml
--cov-band   covariance matrix of adjusted parameters in XML output
              n = -1 for full covariance matrix (implicit value)
              n >= 0 covariances are computed only for bandwidth n
--version
--help
```

Program `gama-local` version is followed by information on compiler used to build the program (apart from GNU `g++` compiler, two other possibilities are `bcc` and `msc` for Borland and Microsoft compilers respectively, when build under Microsoft Windows).

Option `--algorithm` enables to select numerical method used for solution of the adjustment. Implicitly is used Singular Value Decomposition (`svd`), alternatively user can decide for block matrix algorithm GSO by Frantisek Charamza, based on Gram-Schmidt orthogonalization. In both these cases, project equations are solved directly without forming *normal equations*. Third possibility is to select Cholesky decomposition of semidefinite matrix of normal equations (`cholesky`).

Option `--language` selects language used in output protocol. For example, if run with option `--language cz`, `gama-local` prints output results in Czech language using UTF-8 encoding. Implicit value is `en` for output in English.

Option `--encoding` enables to change implicit UTF-8 output encoding to iso-8859-2 (latin-2), iso-8859-2-flat (latin-2 without diacritics), cp-1250 (MS-EE encoding) cp-12251 (Russian encoding).

Option `--angles` selects angular units to be used in output.

Options `--latitude` and/or `--ellipsoid` are used when observed vertical and/or zenith angles need to be transformed into the projection plane. If none of these two options is explicitly used, no corrections are added to horizontal and/or zenith angles. If only one of these options is used, then implicit value for `--latitude` is 45 degrees (50 gons) and implicit ellipsoid is WGS84. Mathematical formulas for the corrections is given in the following section.

Adjustment results (`--text` and `--xml`) can be redirected to standard output if instead of a file name is used "-" string. If no output is given, XML adjustment format is implicitly send to standard output.

Option `--cov-band` is used to reduce the number of computed covariances (cofactors) in XML adjustment output. Implicitly full matrix is written to XML output, which could degrade time efficiency for the `envelope` algorithm for sparse matrix solution. Explicit option for full covariance matrix is `--cov-band -1`, option `--cov-band 0` means that only a diagonal of covariance matrix is written to XML output, `--cov-band 1` results in computing the main diagonal and first codiagonal etc. If higher rank is specified then available, it si reduced do maximum possible value `dim-1`.

### 1.3.1 Reductions of horizontal and zenith angles

For evaluating of reductions of horizontal and zenith angles, `gama-local` computes a helper point  $P_1$  in the center of the network. Horizontal and zenith angles observed at point  $P_2$  are transformed to the projection plane perpendicular to the normal  $z_1$  of the helper point  $P_1$ . Coordinates  $(x_2, y_2)$  of point  $P_2$  are conserved, but its normal  $z_2$  is rotated by the central angle  $2\gamma_{12}$  to be parallel with  $z_1$ .

For observations from point  $P_2$  to point  $P_3$  we denote the zenith angle  $z_{23}^m$  and horizontal direction  $\sigma_{23}^m$ . Now, transformed zenith angle  $z_{23}$  and horizontal direction  $\sigma_{23}$  can be expressed as

$$\begin{aligned}\cos z_{23} &= \cos z_{23}^m \cos 2\gamma_{12} + \sin z_{23}^m \cos(180^\circ - \sigma_{23}^m) \sin \gamma_{12}, \\ \sin(180^\circ - \sigma_{23}^m) \cot \sigma_{23} &= -\cos(180^\circ - \sigma_{23}^m) \cos 2\gamma_{12} + \cot z_{23}^m \sin 2\gamma_{12}\end{aligned}$$

and after arrangement

$$\begin{aligned}\cos z_{23} &= \cos z_{23}^m \cos 2\gamma_{12} - \sin z_{23}^m \cos \sigma_{23}^m \sin \gamma_{12}, \\ \cot \sigma_{23} &= \cot \sigma_{23}^m \cos 2\gamma_{12} + \frac{\cot z_{23}^m \sin 2\gamma_{12}}{\sin \sigma_{23}^m}\end{aligned}$$

These formulas can be simplified for small networks, roughly up to the size of 6 kilometers, where

$$\cos 2\gamma_{12} \approx 1 \quad \text{and} \quad \sin 2\gamma_{12} \approx \frac{2\gamma_{12}''}{\rho''}.$$

and

$$\begin{aligned}\cos z_{23} &= \cos z_{23}^m - \sin z_{23}^m \cos \sigma_{23}^m \frac{2\gamma_{12}''}{\rho''}, \\ \cot \sigma_{23} &= \cot \sigma_{23}^m + \frac{1}{\sin^2 \sigma_{23}^m} \cot z_{23}^m \sin \sigma_{23}^m \frac{2\gamma_{12}''}{\rho''}.\end{aligned}$$

Comparing these expressions with first members of Taylor series

$$f(x) \approx f(x^0) + \frac{df(x^0)}{dx}$$

of functions  $\cos z_{23}$  and  $\cot \sigma_{23}$  for  $z_{23} = z_{23}^m + \Delta z_{23}$  and  $\sigma_{23} = \sigma_{23}^m + \Delta \sigma_{23}$

$$\cos z_{23} = \cos z_{23}^m - \sin z_{23}^m \frac{\Delta z_{23}''}{\rho''}$$

$$\cot \sigma_{23} = \cot \sigma_{23}^m - \frac{1}{\sin^2 \sigma_{23}^m} \frac{\sigma_{23}''}{\varrho''},$$

it holds that  $z_{23} = \cos z_{23}^m + \Delta z_{23}''$  and  $\sigma_{23} = \cos \sigma_{23}^m + \Delta \sigma_{23}''$ .

Equations for reductions of horizontal and zenith angles now can be expressed as

$$z_{23} = \cos z_{23}^m + 2\gamma_{12}'' \cos \sigma_{23}^m$$

$$\sigma_{23} = \sigma_{23}^m - 2\gamma_{12}'' \cot z_{23}^m \sin \sigma_{23}^m.$$

## 1.4 Contributors

The following persons (in chronological order) have made contributions to GNU Gama project: Ales Cepek, Jiri Vesely, Petr Doubrava, Jan Pytel, Chuck Ghilani, Dan Haggman, Mauri Vaisanen, John Dedrum, Jim Sutherland, Zoltan Faludi, Diego Berge, Boris Pihtin, Stephane Kaloustian, Anton Horpynich, Claudio Fontana, Brona Koska and Martin Beckett.

## 1.5 Reporting bugs

Undoubtedly there are numerous bugs remaining, both in the C++ source code and in the documentation. If you find a bug in either, please send a bug report to

[bug-gama@gnu.org](mailto:bug-gama@gnu.org)

We will try to be as quick as possible in fixing the bugs and redistributing the fixes. If you prefer, you can always write directly to [Ales Cepek](#).



## 2 XML input data format for `gama-local`

The input data format for a local geodetic network adjustment (program `gama-local`) is defined in accordance with the definition of Extended Markup Language (XML) for description of structured data. The XML definition can be found at

<http://www.w3.org/TR/REC-xml>

Input data (points, observations and other related information) are described using XML start-end pair tags `<xxx>` and `</xxx>` and empty-element tags `<xxx/>`. The syntax of XML input format is defined in the Document Type Definition (DTD) at

<http://www.gnu.org/software/gama/gama-local.dtd>

and can formally be validated independently on the program `gama-local`.

For parsing the XML input data, `gama-local` uses the XML parser Expat copyrighted by James Clark which is described at

<http://www.jclark.com/xml/expat.html>

Expat is subject to the Mozilla Public License (MPL), or may alternatively be used under the GNU General Public License (GPL) instead.

In the `gama-local` XML input, distances are given in meters, angular values in centigrades and their standard deviations (rms errors) in millimetres or centigrade seconds, respectively. Alternatively angular values in `gama-local` XML input can be given in degrees and seconds (see [Section 2.1 \[Angular units\], page 7](#)). At the end of this document an example of the `gama-local` XML input data object is given.

### 2.1 Angular units

Horizontal angles, directions and zenith angles in `gama-local` XML adjustment input are implicitly given in gons and their standard deviations and/or variances in centicentigons. Gon, also called centesimal grade and Neugrad (German for new grad), is 1/400-th of the circumference. For example

```
<direction from="202" to="416" val="63.9347" stdev="10.0" />
```

The same angular value (direction) can be expressed in degrees as

```
<direction from="202" to="416" val="57-32-28.428" stdev="3.24" />
```

In XML adjustment input degrees are coded as a single string, where degrees (57), minutes (32) and seconds (28.428) are separated by dashes (-) with optional leading sign. Spaces are not allowed inside the string. Gons and degrees may be mixed in a single XML document but one should be careful to supply the information on standard deviations and/or covariances in the proper corresponding units.

Internally `gama-local` works with gons but output can be transformed to degrees using the option `--angles 360`.

### 2.2 Prolog

XML documents may, and should, begin with an XML declaration that specifies the version of XML being used (*prolog*). In the case of `gama-local`, the XML input data are followed by the XML document type declaration:

```
<?xml version="1.0" ?>
<!DOCTYPE gama-local
  SYSTEM "http://www.gnu.org/software/gama/gama-local.dtd">
```

### 2.3 Tags <gama-local> and <network>

A pair tag <gama-local> contains a single pair tag <network> that contains the network definition. The definition of the network is composed of three sections:

- <description> of the network (annotation or comments),
- network <parameters /> and
- <points-observations> section.

The sections <description> and <parameters /> are optional, the section <points-observations> is mandatory. These three sections may be presented in any order and may be repeated several times (in such a case, the corresponding sections are linked together by the software).

The pair tag <network> has two optional attributes `axes-xy` and `angles`. These attributes are used to describe orientation of the `xy` orthogonal coordinate system axes and the orientation of the observed angles and/or directions.

- `axes-xy="ne"` orientation of axes `x` and `y`; value `ne` implies that axis `x` is oriented north and axis `y` is oriented east. Acceptable values are `ne`, `sw`, `es`, `wn` for left-handed coordinate systems and `en`, `nw`, `se`, `ws` for right-handed coordinate systems (default value is `ne`).
- `angles="right-handed"` defines counterclockwise observed angles and/or directions, value `left-handed` defines clockwise observed angles and/or directions (default value is `right-handed`).

Many geodetic systems are right handed with `x` axis oriented east, `y` axis oriented north and counterclockwise angular observations. Example of left-handed orthogonal system with different axes orientation is coordinate system *Krovak* used in the Czech Republic where the axes `x` and `y` are oriented south and west respectively.

GNU Gama can adjust any combination of coordinate and angular systems.

### Example

```
<gama-local>
<network>
  <description> ... </description>
  <parameters ... />
  <points-observations> ... </points-observations>
</network>
</gama-local>
```

It is planned in future versions of the program to allow more <network> tags (analysis of deformations etc.) and definitions of new tags.

## 2.4 Network description

The description of a geodetic network is enclosed in the start-end pair tags `<description>`. Text of the description is copied into the adjustment output and serves for easier identification of results. The text is not interpreted by the program, but it may be helpful for users.

### Example

```
<description>
A short description of a geodetic network ...
</description>
```

## 2.5 Network parameters

The network parameters may be listed with the following optional attributes of an empty-element tag `<parameters />`

- `sigma-apr = "10"` value of a priori reference standard deviation—square root of reference variance (default value 10)
- `conf-pr = "0.95"` confidence probability used in statistical tests (default value 0.95)
- `tol-abs = "1000"` tolerance for identification of gross absolute terms in project equations (default value 1000 mm)
- `sigma-act = "aposteriori"` actual type of reference standard deviation use in statistical tests (`aposteriori` | `apriori`); default value is `aposteriori`
- `update-constrained-coordinates = "no"` enables user to control if coordinates of constrained points are updated in iterative adjustment. If test on linearization fails (see [Section 3.9 \[Linearization\]](#), page 32), Gama tries to improve approximate coordinates of adjusted points and repeats the whole adjustment. Coordinates of constrained points are implicitly not changed during iterations.

Values of the attributes must be given either in the double-quotes (`"..."`) or in the single quotes (`'...'`). There can be *white spaces* (spaces, tabs and new-line characters) between attribute names, values, and the *equal* sign.

### Example

```
<parameters sigma-apr = "15"
             conf-pr   = '0.90'
             sigma-act = "apriori"
             update-constrained-coordinates = "no" />
```

## 2.6 Points and observations

The points and observations section is bounded by the pair tag `<points-observations>` and contains information about points, observed horizontal directions, angles, and horizontal distances, height differences, slope distances, zenith angles, observed vectors and control coordinates.

Optional attributes of the start tag `<points-observations>` allow for the definition of default values of standard deviations corresponding to observed directions, angles, and distances.

- `direction-stdev = "..."` defines the implicit value of observed direction (default value is not defined)
- `angle-stdev = "..."` defines the implicit value of observed angle (default value is not defined)
- `zenith-angle-stdev = "..."` defines the implicit value of observed zenith angle (default value is not defined)
- `distance-stdev = "..."` defines the implicit value of observed horizontal distance (default value is not defined)

Implicit values of standard deviations for the observed distances are calculated from the model with three constants  $a$ ,  $b$ , and  $c$  according to the formula

$$a + bD^c,$$

where  $a$  is a constant part of the model and  $D$  is the observed distance in kilometres. If the constants  $b$  and/or  $c$  are not given, default values of  $b = 0$  and  $c = 1$  will be used.

## Example

```
<points-observations direction-stdev = "10"
                        distance-stdev = "5 3 1" >
  <!-- ... points and observation data ... -->
</points-observations>
```

## 2.7 Points

Points are described by the empty-element tags `<point/>` with the following attributes:

- `id = "..."` is the point identification attribute (mandatory); point identification is not limited to *numbers*; all printable characters can be used in identification.
- `x = "..."` specifies coordinate  $x$
- `y = "..."` specifies coordinate  $y$
- `z = "..."` specifies coordinate  $z$ , point height
- `fix = "..."` specifies coordinates that are fixed in adjustment; acceptable values are  $xy$ ,  $XY$ ,  $z$ ,  $Z$ ,  $xyz$ ,  $XYZ$ ,  $xyZ$  and  $XYz$ .
- `adj = "..."` specifies coordinates to be adjusted (unknown parameters in adjustment); acceptable values are  $xy$ ,  $XY$ ,  $z$ ,  $Z$ ,  $xyz$ ,  $XYZ$ ,  $xyZ$  and  $XYz$ .

With exception of the first attribute (point id), all other attributes are optional. Decimal numbers can be used as needed.

Control coordinates marked using the `fix` parameter are not changed in the adjustment. Uppercase and lowercase notation of coordinates with the `fix` parameter are interpreted the same. Corrections are applied to the unknown parameters identified by coordinates written in lowercase characters given in the `adj` parameter. When the coordinates are written using

uppercase, they are interpreted as *constrained coordinates*. If coordinates are marked with both the `fix` and `adj`, the `fix` parameter will take precedence.

*Constrained coordinates* are used for the regularization of free networks. If the network is not free (fixed network), the *constrained* coordinates are interpreted as other unknown parameters. In classical free networks, the *constrained* points define the regularization constraint

$$\sum dx_i^2 + dy_i^2 = \min.$$

where  $dx$  and  $dy$  are adjusted coordinate corrections and the summation index  $i$  goes over all *constrained* points. In other words, the set of the *constrained* points defines the adjustment of the free network (its shape and size) with a simultaneous transformation to the approximate coordinates of selected points. Program `gama-local` allows the definition of constrained coordinates with 1D leveling networks, 2D and 3D local networks.

## Example

```
<point id="1" y="644498.590" x="1054980.484" fix="xy" />
<point id="2" y="643654.101" x="1054933.801" adj="XY" />
<point id="403" adj="xy" />
```

## 2.8 Set of observations

The pair tag `<obs>` groups together a set of observations which are somehow related. A typical example is a set of directions and distances observed from one stand-point. An observation section contains a set of

- horizontal directions `<direction ... />`
- horizontal distances `<distance ... />`
- horizontal angles `<angle ... />`
- slope distances `<s-distance ... />`
- zenith angles `<z-angle ... />`
- height differences `<dh />`

The band variance-covariance matrix of directions, distances, and angles listed in one `<obs>` section may be supplied using a `<cov-mat>` pair tag with attributes `dim` (dimension) and `band` (bandwidth). The band-width of the diagonal matrix is equal to 0 and a fully-populated variance-covariance matrix has a bandwidth of `dim-1`.

Observation variances and covariances (i.e. an upper-symmetric part of the band-matrix) are written row by row between `<cov-mat>` and `</cov-mat>` tags. If present, the dimension of the variance-covariance matrix must agree with the number of observations.

The following example of variance-covariance matrix with dimension 6 and bandwidth 2 (two nonzero codiagonals and three zero codiagonals)

$$\begin{pmatrix} 1.1 & 0.1 & 0.2 & 0 & 0 & 0 \\ 0.1 & 1.2 & 0.3 & 0.4 & 0 & 0 \\ 0.2 & 0.3 & 1.3 & 0.5 & 0.6 & 0 \\ 0 & 0.4 & 0.5 & 1.4 & 0.7 & 0.8 \\ 0 & 0 & 0.6 & 0.7 & 1.5 & 0.9 \\ 0 & 0 & 0 & 0.8 & 0.9 & 1.6 \end{pmatrix}$$

is coded in XML as

```
<cov-mat dim="6" band="2">
  1.1  0.1  0.2
      1.2  0.3  0.4
          1.3  0.5  0.6
              1.4  0.7  0.8
                  1.5  0.9
                      1.6
</cov-mat>
```

If two or more sets of directions with different orientations are observed from a stand-point, they must be placed in different `<obs>` sections. The value of an orientation angle can be explicitly stated with an attribute `orientation="..."`. Normally, it is more convenient to let the program calculate approximate values of orientations needed for the adjustment. If directions are present, then the attribute `station` must be defined.

Optional attribute `from_dh="..."` enables to enter implicit height of instrument for all observations within the `<obs>` pair tag.

Observed distances are expressed in meters, their standard deviations in millimeters. Observed directions and angles are expressed in centigrades (400) and their standard deviations in centigrade seconds.

Height differences can be entered in the `<obs>` or `<height-differences>` section. If entered in the `<obs>` section, the `dist="..."` parameter is ignored ([Section 2.14 \[Height differences\]](#), [page 15](#)).

## Example

```
<obs from="418">
  <direction to= "2" val="0.0000" stdev="10.0" />
  <direction to="416" val="63.9347" stdev="10.0" />
  <direction to="420" val="336.3190" stdev="10.0" />
  <distance to="420" val="246.594" stdev="5.0" />
</obs>

<obs from="418">
  <direction to= "2" val="0.0000" />
  <direction to="416" val="63.9347" />
  <direction to="420" val="336.3190" />
  <distance to="420" val="246.594" />

  <cov-mat dim="4" band="0">
    100.00 100.00 100.00 25.00
  </cov-mat>
</obs>
```

## 2.9 Directions

Directions are expressed with the following attributes in an empty-element tag `<direction />`

- `to = "..."` target point identification
- `val = "..."` observed direction; see [Section 2.1 \[Angular units\], page 7](#)
- `stdev = "..."` standard deviation (optional)
- `from_dh = "..."` instrument height (optional)
- `to_dh = "..."` reflector/target height (optional)

The standard deviation is an optional attribute. However since all observations in the adjustment must have their weights defined, the standard deviation must be given either explicitly with the attribute `stdev=..."` or implicitly with `<points-observation direction-stdev=..." >` or with a variance-covariance matrix for the given observation set. A similar approach applies to all the observations (distances, angles, etc.)

### Example

```
<direction to= "2" val="0.0000" stdev="10.0" />
<direction to="416" val="63.9347" />
```

## 2.10 Horizontal distances

Distances are written using an empty-element tag `<distance />` with attributes

- `from = "..."` standpoint identification
- `to = "..."` target identification
- `val = "..."` observed horizontal distance
- `stdev = "..."` standard deviation of observed horizontal distance (optional)
- `from_dh = "..."` instrument height (optional)
- `to_dh = "..."` reflector/target height (optional)

Contrary to directions, distances in an observation set (`<obs>`) do not need to share a common stand-point. An example is set of distances observed from several stand-points with a common variance-covariance matrix.

### Example

```
<distance from = "2" to = "1" val = "659.184" />
<distance to ="422" val="228.207" stdev="5.0" />
<distance to ="408" val="568.341" />
```

## 2.11 Angles

Observed angles are expressed with the following attributes of an empty-element tag `<angle />`

- `from = "..."` standpoint identification (optional)
- `bs = "..."` backsight target identification
- `fs = "..."` foresight target identification
- `val = "..."` observed angle; see [Section 2.1 \[Angular units\], page 7](#)
- `stdev = "..."` standard deviation (optional)

- `from_dh` = "... " instrument height (optional)
- `bs_dh` = "... " backsight reflector/target height (optional)
- `fs_dh` = "... " foresight reflector/target height (optional)

Similar to distance observations, one observation set may group angles observed from several standpoints.

## Example

```
<angle from="433" bs="422" fs="402" val="128.6548" stdev="14.1"/>
<angle from="433" bs="422" fs="402" val="128.6548" />
<angle bs="422" fs="402" val="128.6548" stdev="14.1"/>
<angle bs="422" fs="402" val="128.6548"/>
```

## 2.12 Slope distances

Slope distances (space distances) are written using an empty-element tag `<s-distance />` with attributes

- `from` = "... " standpoint identification (optional)
- `to` = "... " target identification
- `val` = "... " observed slope distance
- `stdev` = "... " standard deviation of observed slope distance (optional)
- `from_dh` = "... " instrument height (optional)
- `to_dh` = "... " reflector/target height (optional)

Similar to horizontal distances, one observation set may group slope distances observed from several standpoints.

## Example

```
<s-distance from = "2" to = "1" val = "658.824" />
<s-distance to ="422" val="648.618" stdev="5.0" />
<s-distance to ="408" val="482.578" />
```

## 2.13 Zenith angles

Zenith angles are written using an empty-element tag `<z-angle />` with the following attributes

- `from` = "... " standpoint identification (optional)
- `to` = "... " target identification
- `val` = "... " observed zenith angle; see [Section 2.1 \[Angular units\]](#), page 7
- `stdev` = "... " standard deviation of observed zenith angle (optional)
- `from_dh` = "... " instrument height (optional)
- `to_dh` = "... " reflector/target height (optional)

Similar to horizontal distances, one observation set may group zenith angles observed from several standpoints.

## Example

```
<z-angle from = "2" to = "1" val = "79.6548" />
<z-angle to ="422" val="85.4890" stdev="5.0" />
<z-angle to ="408" val="95.7319" />
```

## 2.14 Height differences

A set of observed leveling height differences is described using the start-end tag `<height-differences>` without parameters. The `<height-differences>` tag can contain a series of height differences (at least one) and can optionally be supplied with a variance-covariance matrix. Single height differences are defined with empty tags `<dh />` having the following attributes:

- `from = "..."` standpoint identification
- `to = "..."` target identification
- `val = "..."` observed leveling height difference
- `stdev = "..."` standard deviation of levelling elevation and
- `dist = "..."` distance of leveling section (in kilometers)

If the value of standard deviation is not present and length of leveling section (in kilometres) is defined, the value of standard deviation is computed from the formula

$$m_{dh} = m_0 \sqrt{D_{km}}.$$

If the value of standard deviation of the height difference is defined, information on leveling section length is ignored. A third possibility is to define a common variance-covariance matrix for all elevations in the set.

## Example

```
<height-differences>
  <dh from="A" to="B" val=" 25.42" dist="18.1" />
  <dh from="B" to="C" val=" 10.34" dist=" 9.4" />
  <dh from="C" to="A" val="-35.20" dist="14.2" />
  <dh from="B" to="D" val="-15.54" dist="17.6" />
  <dh from="D" to="E" val=" 21.32" dist="13.5" />
  <dh from="E" to="C" val="  4.82" dist=" 9.9" />
  <dh from="E" to="A" val="-31.02" dist="13.8" />
  <dh from="C" to="D" val="-26.11" dist="14.0" />
</height-differences>
```

## 2.15 Control coordinates

Control (known) coordinates are described by the start-end pair tag `<coordinates>`. A series of points with known coordinates can be defined using the `<point />` tag. The variance-covariance matrix for the entire set of points can be created with a single `<cov-mat>` tag. In the `<point />` tags, a point identification (ID) and its coordinates (x, y and z) must be listed. Although the order of the `<point />` tag attributes is irrelevant in the corresponding variance-covariance matrix, the expected order of the coordinates is x, y and z (the horizontal coordinates x, y, or the height z might be missing, but not both). The type of the points may be defined either directly within the `<coordinates>` tag or outside of it.

### Example

```
<coordinates>
  <point id="1" x="100.00" y="100.00" />
  <point id="2" z="200.00" y="200.00" x="200.00" />
  <point id="3" z="300.00" />
  <cov-mat dim="6" band="5" >
    ... <!-- covariances for 1x 1y 2x 2y 2z 3z -->
  </cov-mat>
</coordinates>
```

## 2.16 Coordinate differences (vectors)

Observed coordinate differences describe relative positions of station pairs (vectors). Contrary to the observed coordinates, the variance-covariance matrix of the coordinate differences always describes all three elements of the 3D vectors.

Optional attributes of empty element tag `<vec>` for describing instrument and/or target height are

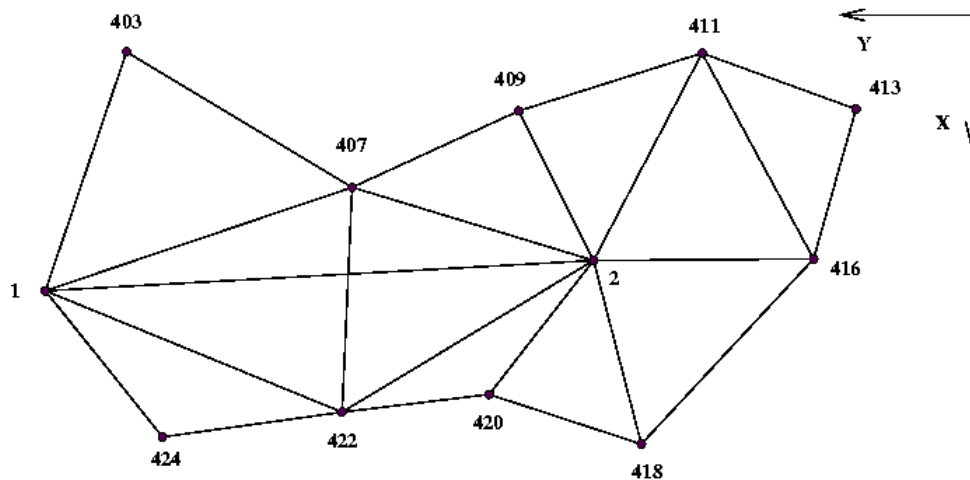
- `from_dh = "..."` instrument height
- `to_dh = "..."` target height

### Example

```
<vectors>
  <vec from="id1" to="id2" dx="..." dy="..." dz="..." />
  <vec from="id2" to="id3" dx="..." dy="..." dz="..." />
  ...
  <cov-mat dim="..." band="..." >
    ..
  </cov-mat>
</vectors>
```

## 2.17 Example of local geodetic network

The XML input data format should be now reasonably clear from the following sample geodetic network. This example is taken from user's guide to Geodet/PC by Frantisek Charamza.



```
<?xml version="1.0" ?>
<!DOCTYPE gama-local
  SYSTEM "http://www.gnu.org/software/gama/gama-local.dtd">

<gama-local>
<network axes-xy="sw">

<description>
XML input stream of points and observation data for program Gama
<!-- this is a XML comment -->
</description>

<!-- parameters are expressed with empty-element tag -->

<parameters sigma-act = "aposteriori" />

<points-observations>

<!-- fixed point, constrained point -->

<point id="1" y="644498.590" x="1054980.484" fix="xy" />
<point id="2" y="643654.101" x="1054933.801" adj="XY" />

<!-- computed / adjusted points -->
```

```

<point id="403" adj="xy" />
<point id="407" adj="xy" />
<point id="409" adj="xy" />
<point id="411" adj="xy" />
<point id="413" adj="xy" />
<point id="416" adj="xy" />
<point id="418" adj="xy" />
<point id="420" adj="xy" />
<point id="422" adj="xy" />
<point id="424" adj="xy" />

<obs from="1">
  <direction to= "2" val= "0.0000" stdev="10.0" />
  <direction to="422" val= "28.2057" stdev="10.0" />
  <direction to="424" val= "60.4906" stdev="10.0" />
  <direction to="403" val="324.3662" stdev="10.0" />
  <direction to="407" val="382.8182" stdev="10.0" />
  <distance to= "2" val= "845.777" stdev="5.0" />
  <distance to="422" val= "493.793" stdev="5.0" />
  <distance to="424" val= "288.301" stdev="5.0" />
  <distance to="403" val= "388.536" stdev="5.0" />
  <distance to="407" val= "498.750" stdev="5.0" />
</obs>

<obs from="2">
  <direction to= "1" val="0.0000" stdev="10.0" />
  <direction to="407" val="22.2376" stdev="10.0" />
  <direction to="409" val="73.8984" stdev="10.0" />
  <direction to="411" val="134.2090" stdev="10.0" />
  <direction to="416" val="203.0706" stdev="10.0" />
  <direction to="418" val="287.2951" stdev="10.0" />
  <direction to="420" val="345.6928" stdev="10.0" />
  <direction to="422" val="368.9908" stdev="10.0" />
  <distance to="407" val="388.562" stdev="5.0" />
  <distance to="409" val="257.498" stdev="5.0" />
  <distance to="411" val="360.282" stdev="5.0" />
  <distance to="416" val="338.919" stdev="5.0" />
  <distance to="418" val="292.094" stdev="5.0" />
  <distance to="420" val="261.408" stdev="5.0" />
  <distance to="422" val="452.249" stdev="5.0" />
</obs>

<obs from="403">
  <direction to= "1" val="0.0000" stdev="10.0" />
  <direction to="407" val="313.5542" stdev="10.0" />
  <distance to="407" val="405.403" stdev="5.0" />
</obs>

```

```
<obs from="407">
  <direction to= "1" val="0.0000" stdev="10.0" />
  <direction to="403" val="55.1013" stdev="10.0" />
  <direction to="409" val="193.3410" stdev="10.0" />
  <direction to= "2" val="239.4204" stdev="10.0" />
  <direction to="422" val="323.5443" stdev="10.0" />
  <distance to="409" val="281.997" stdev="5.0" />
  <distance to="422" val="346.415" stdev="5.0" />
</obs>

<obs from="409">
  <direction to= "2" val="0.0000" stdev="10.0" />
  <direction to="407" val="102.2575" stdev="10.0" />
  <direction to="411" val="310.1751" stdev="10.0" />
  <distance to="411" val="296.281" stdev="5.0" />
</obs>

<obs from="411">
  <direction to= "2" val="0.0000" stdev="10.0" />
  <direction to="409" val="49.8647" stdev="10.0" />
  <direction to="413" val="291.4953" stdev="10.0" />
  <direction to="416" val="337.6667" stdev="10.0" />
  <distance to="413" val="252.266" stdev="5.0" />
  <distance to="416" val="360.449" stdev="5.0" />
</obs>

<obs from="413">
  <direction to="411" val="0.0000" stdev="10.0" />
  <direction to="416" val="295.3582" stdev="10.0" />
  <distance to="416" val="239.745" stdev="5.0" />
</obs>

<obs from="416">
  <direction to= "2" val="0.0000" stdev="10.0" />
  <direction to="411" val="68.8065" stdev="10.0" />
  <direction to="413" val="117.9922" stdev="10.0" />
  <direction to="418" val="348.1606" stdev="10.0" />
  <distance to="418" val="389.397" stdev="5.0" />
</obs>

<obs from="418">
  <direction to= "2" val="0.0000" stdev="10.0" />
  <direction to="416" val="63.9347" stdev="10.0" />
  <direction to="420" val="336.3190" stdev="10.0" />
  <distance to="420" val="246.594" stdev="5.0" />
</obs>
```

```
<obs from="420">
  <direction to= "2" val="0.0000" stdev="10.0" />
  <direction to="418" val="77.9221" stdev="10.0" />
  <direction to="422" val="250.1804" stdev="10.0" />
  <distance to="422" val="228.207" stdev="5.0" />
</obs>

<obs from="422">
  <direction to= "2" val="0.0000" stdev="10.0" />
  <direction to="420" val="26.8834" stdev="10.0" />
  <direction to="424" val="225.7964" stdev="10.0" />
  <direction to= "1" val="259.2124" stdev="10.0" />
  <direction to="407" val="337.3724" stdev="10.0" />
  <distance to="424" val="279.405" stdev="5.0" />
</obs>

<obs from="424">
  <direction to= "1" val="0.0000" stdev="10.0" />
  <direction to="422" val="134.2955" stdev="10.0" />
</obs>

</points-observations>

</network>
</gama-local>
```

### 3 Network adjustment with gama-local

Adjustment of local geodetic network is a classical case of *adjustment of indirect observations*. After estimation of approximate values of unknown parameters (coordinates of points) and linearization of functions describing relations between observations and parameters we solve linear system of equations

$$\mathbf{Ax} = \mathbf{b} + \mathbf{v}, \quad (1)$$

where  $\mathbf{A}$  is coefficient matrix,  $\mathbf{b}$  is vector of absolute terms (right hand side) and  $\mathbf{v}$  is vector of residuals. This system is (generally) overdetermined and we seek the solution  $\mathbf{x}$  satisfying the basic criterion of Least Squares

$$\mathbf{v}'\mathbf{P}\mathbf{v} = \min, \quad (2)$$

where  $\mathbf{P}$  is weight matrix. This criterion unambiguously defines the shape of adjusted network.

In the case of *free network* the system (1) is singular (matrix  $\mathbf{A}$  has linearly dependent columns) and we have to define second regularization criterion

$$\sum_{i \in \Omega} x_i^2 = \min, \quad (3)$$

stating that at the same time we demand that the sum of squares corrections of selected parameters is minimal (corrections of unknown parameters with indexes from the set  $\Omega$ ). Geometrically this criterion is equivalent to adjustment of the network according to (2) with simultaneous transform to the selected set of fiducial points. This transformation does not change the shape of adjusted network.

Often it is advantageous to work with a *homogenized system*, ie. with the system of project equations in which coefficient of each row and absolute term are multiplied by square root of the weight of corresponding observation.

$$\tilde{\mathbf{A}}\mathbf{x} = \tilde{\mathbf{b}}, \quad (4)$$

where  $\tilde{\mathbf{A}} = \mathbf{P}^{1/2}\mathbf{A}$ ,  $\tilde{\mathbf{b}} = \mathbf{P}^{1/2}\mathbf{b}$ . Symbol  $\mathbf{P}^{1/2}$  denotes diagonal matrix of square roots of observation weights (or Cholesky decomposition of covariance matrix in the case of correlated observations). To criterion (2) corresponds in the case of homogenized system criterion

$$\tilde{\mathbf{v}}'\mathbf{v} = \min. \quad (5)$$

Normal equations are clearly equivalent for both systems.

$$(\mathbf{A}'\mathbf{P}\mathbf{A})\mathbf{x} = (\mathbf{A}'\mathbf{P}\mathbf{b}) \quad \equiv \quad (\tilde{\mathbf{A}}'\tilde{\mathbf{A}})\mathbf{x} = (\tilde{\mathbf{A}}'\tilde{\mathbf{b}}).$$

Between weight coefficients of the original system (1) and homogenized system (4) are the following relations

$$\begin{aligned} q_{x_i} &= \tilde{q}_{x_i}, & i &= 1, \dots, n, \\ q_{L_j} &= \tilde{q}_{L_j}/p_j, & j &= 1, \dots, m, \\ q_{v_k} &= \tilde{q}_{v_k}/p_k = (1 - \tilde{q}_{L_k})/p_k = 1/p_k - q_{L_k}, & k &= 1, \dots, m. \end{aligned}$$

### 3.1 Approximate coordinates

For computation of coefficients in system (1) (ie. during linearization) we need, first of all, an estimate of approximate coordinates of points and approximate values of orientations of observed directions sets.

Approximate values of unknown parameters are usually not known and we have to compute them from the available observations. For approximate value of orientation program `gama-local` uses median of all estimates from the given set of directions to the points with known coordinates. Median is less sensitive to outliers than arithmetic mean which is normally used for approximate estimate of orientations

During the phase of computation of approximate coordinate of points, program `gama-local` walks through the list of computed points and for each point gathers all determining elements pointing to points with known or previously computed coordinates. Determining elements are

**outer bearing** (oriented half-line) starting from the point with known coordinates and pointing to the computed point

**distance** between given and computed points

**inner angle** with vertex in the computed point and arms intersecting given points

For all combinations of determining elements program `gama-local` computes intersections and estimates approximate coordinates as the median of all available solutions.

If at least one point was resolved while iterating through the list, the whole cycle is repeated.

If no more coordinates can be solved using intersections and points with unknown coordinates are remaining, program tries to compute coordinates of unresolved points in a local coordinates system and obtain their coordinates using similarity transformation. If a transformation succeeds to resolve coordinates at least one computed point and there are still some points without coordinates left, the whole process is repeated. Classes for computation of approximate coordinates have been written by Jiri Vesely.

If program `gama-local` fails to compute approximate coordinates of some of the network points, they are eliminated from the adjustment and they are listed in the output listing.

With the outlined strategy, program `gama-local` is able to estimate approximate coordinates in most of the cases we normally meet in surveying profession. Still there are cases in which the solution fails. One example is an inserted horizontal traverse with sets of observed direction on both ends but without a connecting observed distance. The solution of approximate coordinates can fail when there is a number of gross error for example resulting from confusion of point identifications but in normal situations, leaving computation of approximate coordinates on program `gama-local` is recommended.

#### Example

```
Computation of approximate coordinates of points
*****
```

```
Number of points with given coordinates:      2
Number of solved points                       :      2
Number of observations                        :      4
```

```
-----
Successfully solved points      :      0
Remaining unsolved points      :      2
```

```
List of unresolved points
*****
422
424
```

### 3.2 Gross absolute terms

One of parameters in XML input of program `gama-local` is tolerance `tol-abs` for detecting of gross absolute terms in project equations. Observations with outlying absolute terms are always excluded from adjustment.

For measured distances program tests difference between observed value  $d_i$  and distance computed from approximate coordinates  $d_0$

$$|d_i - d_0| > \text{tol} - \text{abs},$$

for observed directions program `gama-local` tests transverse deviation corresponding to absolute term  $b_i$  from project equations (1)

$$|b_i|d_0 > \text{tol} - \text{abs}$$

and similarly for angles, program tests the greater of two deviations corresponding to left and right distances (left and right arm of the angle)

$$|b_i| \max\{d_{0_l}, d_{0_r}\} > \text{tol} - \text{abs}.$$

Default value of parameter `tol-abs` is 1000 mm.

### Example

```
Outlying absolute terms in project equations
*****
```

i	standpoint	target	observed	absolute
			value	term
2	103	104 dir.	301.087900	-9989.1

```
Observations with outlying absolute terms removed
```

### 3.3 Parameters of statistical analysis

Program `gama-local` uses two basic statistical parameters

- confidence probability  $P$  (default value is 95%, see parameter `conf-pr`) and
- actual type of reference standard deviation  $m_{0a}$  (parameter `typ-m0`).

Confidence probability determines significance level on which statistical tests of adjusted quantities are carried. Actual type of reference standard deviations  $m_{0a}$  specifies whether during statistical analysis we use a priori reference standard deviation  $m_0$  or a posteriori estimate  $m'_0$ .

We can choose only the type of actual reference standard deviation ( $m_0$  or  $m'_0$ ) but not its value. The value corresponds to a priori given value of reference standard deviation or to the results of adjustment. On the type of actual reference standard deviation depends the choice of density functions of stochastic quantities in statistical analysis of the adjustment.

**A priori reference standard deviation**  $m_0$  is used in the cases when we know its value in advance and with sufficient reliability. Another situation when  $m_0$  is used are networks with low number of degrees of freedom (poorly overdetermined systems) or when veen degrees of freedom is zero. Examples may be analysis of network models etc.

**A posteri estimate of reference standard deviation**  $m'_0$  is used in cases when a priori value of reference standard deviation  $m_0$  is not known and when degrees of freedom is sufficiently high and reliable for empirical estimate of  $m'_0$ .

The standard deviation of an adjusted quantity  $\theta$  is computed in dependece on the choice of actual type of reference standard deviation  $m_{0a}$  according to formula

$$m_{\theta_i} = m_{0a} \sqrt{q_{\theta_{ii}}},$$

where  $q_{\theta_{ii}}$  is weight coefficient (cofactor) of the  $i$ -th adjusted unknown parameter (coordinate or orientation,  $\theta = x_i$ ) or  $i$ -th adjusted observation (distance, direction,  $\dots, \theta = L_i$ ).

Apart from standard deviation  $m_\theta$ , program `gama-local` computes for adjusted quantity  $\theta$  its *confidence interval*  $(\Theta_1, \Theta_2)$  in which the real value  $\Theta$  is located with probability  $P$

$$P(\Theta_1 < \Theta < \Theta_2) = P,$$

$$\Theta_1 = \theta - k_p m_\theta, \quad \Theta_2 = \theta + k_p m_\theta,$$

where coefficient  $k_p$  depends on confidence probability  $P$  and in the case of low number of degrees of freedom on the choice of actual type of reference standard deviation  $m_{0a}$ .

Coefficient  $k_p$  is computed for  $m_{0a} = m_0$  as critical value of normal distribution for probability  $\alpha/2$ , for the case of choice  $m_{0a} = m'_0$  as critical value of Student distribution on confidence level  $\alpha/2$  with  $\tau$  degrees of freedom

$$k_p = \begin{cases} u_{\alpha/2} & \text{if } m_{0a} = m_0, \\ t_{\alpha/2, \tau} & \text{if } m_{0a} = m'_0. \end{cases}$$

Similarly confidence ellipses for adjusted points are defined in the following text.

### 3.4 Test on the reference standard deviation

Null hypothesis  $H_0 : m_0 = m'_0$  is tested versus alternative hypothesis  $H_1 : m_0 \neq m'_0$ . Test criterion is ratio of a posteriori estimate of reference standard deviation

$$m'_0 = \sqrt{\mathbf{v}'\mathbf{P}\mathbf{v}/\tau}$$

and a priori reference standard deviation  $m_0$  (input data parameter `m0-apr`). For given significance level  $\alpha$  lower and upper bounds of interval  $(L, U)$  are computed so, that if hypothesis  $H_0$  is true, probabilities  $P(m'_0/m_0 \leq D)$  and  $P(m'_0/m_0 \geq H)$  are equal to  $\alpha/2$ . Lower and upper bounds of the interval are computed as

$$L = \sqrt{(\chi_{1-\alpha/2, \tau}^2/\tau)}, \quad U = \sqrt{(\chi_{\alpha/2, \tau}^2/\tau)}.$$

Probability

$$P(L < m'_0/m_0 < U) = \text{conf} - \text{pr}$$

is by default 95%, this corresponds to 5% confidence level test.

Exceeding the upper limit  $H$  of the confidence interval can be caused even by a single gross error (one outlying observation). Method of Least Squares is generally very sensitive to presence of outliers. Safely can be detected only one observation whose elimination leads to maximal decrease of a posteriori estimate of reference standard deviation

$$m''_0 = \sqrt{(\mathbf{v}'\mathbf{P}\mathbf{v} - \delta)/(\tau - 1)}, \quad \delta = \max(v_i^2/q_{v_i}), \quad (6)$$

where

$$q_{v_i} = 1/p_i - q_{L_i} \quad (7)$$

is weight coefficient of  $i$ -th residual. If the set of observations contains only one gross error, the outlying observation is likely to be detected, but this can not be guaranteed.

In addition, program `gama-local` computes a posteriori estimate of reference standard deviation separately for horizontal distances and directions and/or angles after formula from

$$m'_{0t} = \sqrt{\sum \tilde{v}_{i_t}^2 / \sum \tilde{q}_{v_{i_t}}}, \quad t = d, s,$$

where symbol  $t$  denotes observed distances, directions and/or angles.

#### Example

```
m0 apriori : 10.00
m0' empirical: 9.64 [pvv] : 3.43560e+03
```

During statistical analysis we work

- with empirical standard deviation 9.64
- with confidence level 95 %

```
Ratio m0' empirical / m0 apriori: 0.964
95 % interval (0.773, 1.227) contains value m0'/m0
```

```

m0'/m0 (distances): 0.997   m0'/m0 (directions): 0.943

Maximal decrease of m0''/m0 on elimination of one observation: 0.892

Maximal studentized residual 2.48 exceeds critical value 1.95
on significance level 5 % for observation #35
<distance from="407" to="422" val="346.415" stdev="5.0" />

```

### 3.5 Information on points

Program `gama-local` lists separately review of coordinates of fixed and adjusted points; adjusted *constrained* coordinates are marked with `*`; see equation (3). Adjusted coordinate standard deviations  $m_x$  and  $m_y$ , and values for computing confidence intervals are given in the listing of adjusted coordinates (Section 3.3 [Statistical analysis], page 24). In the review index  $i$  is the index of unknown  $x_i$  from the system of project equations (1) corresponding to the point coordinates  $x$  and  $y$ .

#### Example

```

Fixed points
*****

```

point	x	y
1	1054980.484	644498.590
2	1054933.801	643654.101

```

Adjusted coordinates
*****

```

i	point	approximate value	correction [m]	adjusted value	std.dev	conf.i. [mm]
	422					
2	x	1055167.22747	-0.00510	1055167.22237	2.7	5.4
3	y	644041.46119	0.00023	644041.46142	2.5	5.1
	424					
4	X *	1055205.41198	-0.00056	1055205.41142	3.1	6.3
5	Y *	644318.24425	-0.00125	644318.24300	3.6	7.2

For adjusted points, program summarizes information on standard ellipses, confidence ellipses, mean square positional errors ( $m_p$ ), mean coordinate errors ( $m_{xy}$ ) and coefficients  $g$  characterizing position of approximate coordinates with regard to the confidence ellipse.

## Example

Mean errors and parameters of error ellipses

\*\*\*\*\*

point =====	mp [mm] ==	mxy [mm] =====	mean error ellipse ==== a [mm] b alpha[g]			conf.err. ellipse ==== a' [mm] b'		g =====
422	3.6	2.6	2.7	2.5	187.0	6.8	6.4	0.8
424	4.7	3.4	3.7	2.9	131.8	9.5	7.4	0.2
403	5.7	4.0	4.3	3.6	78.9	11.0	9.3	1.1

Mean square positional error  $m_p$  and mean coordinate error ( $m_{xy}$ ) are computed as

$$m_p = \sqrt{m_y^2 + m_x^2}, \quad m_{xy} = m_p/\sqrt{2},$$

where  $m_y^2$  and  $m_x^2$  are squares of standard deviations (variances) of adjusted points coordinates.

Semimajor and semiminor axes of standard ellipse are denoted as  $a$  and  $b$  in the listing, bearing of semimajor axis is denoted as  $\alpha$  and they are computed from covariances of adjusted coordinates

$$a = \sqrt{\frac{1}{2}(\text{cov } yy + \text{cov } xx + c)}, \quad b = \sqrt{\frac{1}{2}(\text{cov } yy + \text{cov } xx - c)},$$

$$c = \sqrt{(\text{cov } xx - \text{cov } yy)^2 + 4(\text{cov } xy)^2},$$

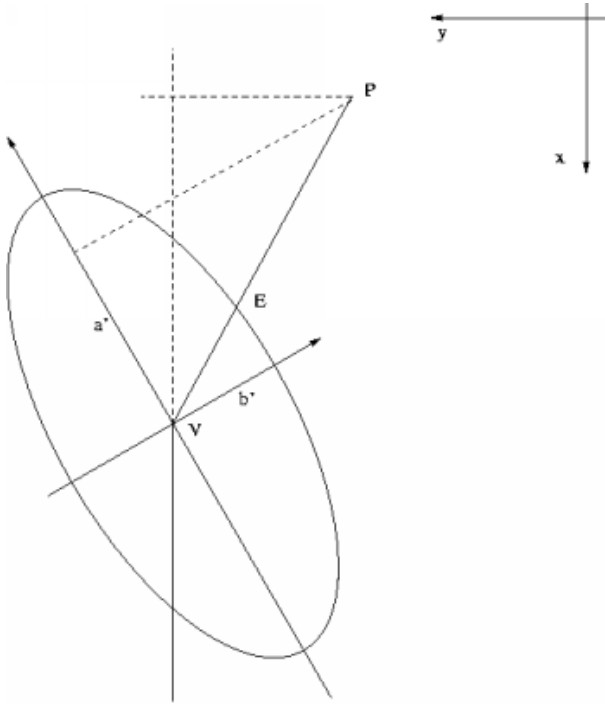
$$\tan 2\alpha = 2(\text{cov } xy)/(\text{cov } xx - \text{cov } yy).$$

The angle  $\alpha$  (the bearing of semimajor axis) is measured clockwise from X axis.

Probability that standard ellipse covers real position of a point is relatively low. For this reason program `gama-local` computes extra *confidence ellipse* for which the probability of covering real point position is equal to the given confidence probability. Both ellipses are located in the same center, they share the same bearing of semimajor axes and they are similar. For lengths of their semi-axis holds

$$a' = k_p a, \quad b' = k_p b,$$

where  $k_p$  is a coefficient computed for the given probability  $P$  as defined in [Section 3.3 \[Statistical analysis\]](#), page 24.



Position of approximate coordinates of an adjusted point with respect to its confidence ellipse is described by two points  $P$  and  $V$  where point  $P$  depicts approximate coordinates and  $V$  adjusted coordinates. Point  $E$  is the intersection of oriented half-line  $VP$  and the confidence ellipse. Coefficient  $g$  is defined as the ration of abscissae

$$g = \overline{VP} / \overline{VE}.$$

Three cases are possible

$g < 1$  approximate coordinates of adjusted point are located inside the confidence ellipse

$g = 1$  approximate coordinates of adjusted point are located on the confidence ellipse

$g > 1$  approximate coordinates of adjusted point are outside the confidence ellipse

The coefficient  $g$  is calculated from formula

$$g = \sqrt{(a_0/a')^2 + (b_0/b')^2}$$

where

$$b_0 = \delta_y \cos \alpha - \delta_x \sin \alpha, \quad a_0 = \delta_y \sin \alpha - \delta_x \cos \alpha$$

symbol  $\delta$  is used for correction of approximate coordinates and  $\alpha$  is bearing of confidence ellipse semimajor axis.

If network contains sets of observed directions, program writes information on corresponding adjusted orientations, standard deviations and confidence intervals. Index  $i$  is the same as in the case of adjusted coordinates the index of  $i$ -th adjusted unknown in the project equations.

## Example

Adjusted bearings  
\*\*\*\*\*

i	standpoint	approximate value [g]	correction [g]	adjusted value [g]	std.dev	conf.i. [cc]
1	1	296.484371	-0.000917	296.483454	5.1	10.3
10	2	96.484371	0.000708	96.485079	5.1	10.4
21	403	20.850571	-0.001953	20.848618	8.8	17.7

## 3.6 Adjusted observations and residuals

In the review of adjusted observations program `gama-local` prints index of the observation, index of the row in matrix **A** in the system (1), identifications of standpoint and target point, type of the observation, its approximate and adjusted value, standard deviation and confidence interval.

## Example

Adjusted observations  
\*\*\*\*\*

i	standpoint	target		observed value	adjusted [m g]	std.dev	conf.i. [mm cc]
1	1	2	dis.	845.77700	845.77907	3.0	6.1
2		422	dir.	28.205700	28.205613	5.1	10.3
3		424	dir.	60.490600	60.491359	6.7	13.6

Review of residuals serves for analysis of observations and contains values of normalized or studentized residuals (depending on type of  $m_{0a}$  used) and three characteristics. These are coefficient **f** identifying weak network elements and estimates of real error of observation **e-obs** and real error of its adjusted value **e-adj**, see definition in the following text.

If normalized or studentized residual exceeds critical value for the given confidence probability, it is marked in the review with symbol **c** (critical) and maximal normalized or studentized residual is marked with symbol **m**.

## Example

Residuals and analysis of observations  
\*\*\*\*\*

i	standpoint	target	f [%]	v	v'	e-obs.	e-adj.	
1	1	2	dir.	47.4	9.170	1.1	12.7	3.5

2	422 dir.	47.0	-0.873	0.1	-1.2	-0.3
3	424 dir.	30.3	7.588	1.1	14.8	7.2

### 3.6.1 Test on normal distribution of homogenized residuals

Repeated observations often display a normal frequency distribution. Residual of observed quantities are linear function real errors. From presumption of normal distribution of real errors follows that homogenized residuals should have normal distribution as well.

Program `gama-local` estimates mean value  $E(\tilde{v})$  and estimate of variance  $V(\tilde{v})$  for the vector of homogenized residuals

$$E(\tilde{v}) = \frac{1}{N} \sum_{i=1}^N \tilde{v}_i, \quad V(\tilde{v}) = E(\tilde{v}^2) - (E(\tilde{v}))^2.$$

Vector of homogenized residuals transforms to *normalized (standardized) vector of residuals*

$$\nu_i = \frac{\tilde{v}_i - E(\tilde{v})}{\sqrt{V(\tilde{v})}}.$$

Using Kolmogorov-Smirnov test program `gama-local` verifies assumption of normality of elements of vector  $\nu$ . Result of the test is a value saying what is the probability that elements of vector  $\nu$  are a random sample from normal distribution  $N(0, 1)$ .

Kolmogorov-Smirnov test for one sample is based on maximal difference between empirical and theoretical cumulative distribution function (normal distribution  $N(0, 1)$  in our case). For random sample with  $N$  elements  $X_1, X_2, \dots, X_N$  from the population with cumulative distribution function  $F(x)$  we form empirical cumulative distribution function

$$S_N(x) = (\text{number of elements } X_1, X_2, \dots, X_N \text{ which are } \leq x)/N,$$

If we denote

$$D = \max_{-\infty < x < \infty} |S_N(x) - F(x)|,$$

the testing criterion  $D\sqrt{N}$  has limit of Kolmogorov-Smirnov distribution. Some critical values of testing criterion  $D\sqrt{N}$  computed from the *KS* distribution are given in the following table

	0.005	0.010	0.025	0.050	0.100
Lower	0.42	0.44	0.48	0.52	0.57
Upper	1.73	1.63	1.48	1.36	1.22

## 3.7 Identification of weak network elements

When planning observations in a geodetic network we always try to guarantee that all observed elements are checked by other measurements. Only with redundant measurements it is possible to adjust observations and possibly remove blunders that might otherwise totally corrupt the whole set of measurements. Apart from sufficient number of redundant observations the degree of control of single observed elements is given by the network configuration, ie. its geometry.

Less controlled observations represent weak network elements and they can in extreme cases even disable detection of gross observational errors as it is in the case of uncontrolled observations. There are two limit cases of observation control

**fully controlled observation** as is for example an observed distance between two fixed points (standard deviation of the adjusted element is zero; standard deviation of the residual equals to the standard deviation if the observation) and

**uncontrolled observations** as is a free polar bar for example (standard deviation of adjusted value is equal to standard deviation of observed quantity; residual and standard deviation of the residual are zero).

Weakly controlled or uncontrolled observations can result even from elimination of certain suspicious observations during analysis of adjustment.

Standard deviation of adjusted observations is less than standard deviation of the measurement. Degree of observation control in network is defined as coefficient

$$f = 100 \frac{m_\ell - m_L}{m_\ell}, \quad (8)$$

where  $m_\ell$  is standard deviation of observed quantity and  $m_L$  is standard deviation computed from a posteriori reference standard deviation  $m_0$ . We consider observed network element to be

**uncontrolled** if  $f < 0.1$  (in listing marked with letter **u**),

**weakly controlled** if  $0.1 \leq f < 5$  (in listing marked with letter **w**).

### 3.8 Estimation of real errors

According to previous section we can consider an observation to be controlled if its coefficient  $f > 0.1$ . Any controlled observation can be eliminated from the network without corrupting the network consistency—network reduced by one controlled observation can be adjusted and all unknown parameters can be computed without the eliminated observation.

Estimate of real error of  $i$ -th observation is defined as

$$\varepsilon_{\ell_i} = L_i^{red} - \ell_i, \quad (9)$$

where  $\ell_i$  is value of  $i$ -th observation and  $L_i^{red}$  is value of  $i$ -th network element computed from adjusted coordinates and/or orientations of the reduced network. Similarly is defined the estimate of real error of a residual

$$\varepsilon_{v_i} = L_i^{red} - L_i. \quad (10)$$

Adjustment results are the best statistical estimate of unknown parameters that we have. This holds true even for adjustment of *reduced* network which is not influenced by real error of  $i$ -th observation. On favourable occasions differences (9) and (10) can help to detect blunders but to interpret these estimates as *real errors* is possible only with substantial exaggeration. These estimates fail when there are more than one significant observational error. Generally holds that the weaker the element is controlled in network the less reliable these estimates are.

Estimate of real error of an observation computes program `gama-local` as

$$\varepsilon_{\ell_i} = v_i / (p_i q_{v_i})$$

and estimate of real error of a residual as

$$\varepsilon_{v_i} = \varepsilon_{l_i} - v_i.$$

### 3.9 Test on linearization

Mathematical model of geodetic network adjustment in `gama-local` is defined as a set of known real-valued differentiable functions

$$\mathbf{L}^* = \varphi(\mathbf{X}^*), \quad (11)$$

where  $\mathbf{L}^*$  is a vector of theoretical correct observations and  $\mathbf{X}^*$  is a vector of correct values of parameters. For the given sample set of observations  $\mathbf{L}$  and the unknown vector of residuals  $\mathbf{v}$  we can express the estimate of parameters  $\mathbf{X}$  as a nonlinear set of equations

$$\mathbf{L} + \mathbf{v} = \varphi(\mathbf{X}). \quad (12)$$

With approximate values  $\mathbf{X}_0$  of unknown parameters

$$\mathbf{X} = \mathbf{X}_0 + \mathbf{x}$$

we can linearize the equations (12)

$$\mathbf{L} + \mathbf{v} = \varphi(\mathbf{X}_0) + \left. \frac{\partial \varphi}{\partial \mathbf{X}} \right|_{\mathbf{x}=\mathbf{x}_0} \mathbf{x}$$

yielding the linear set of equations (1) where

$$\mathbf{A} = \left. \frac{\partial \varphi}{\partial \mathbf{X}} \right|_{\mathbf{x}=\mathbf{x}_0} \quad \text{and} \quad \mathbf{b} = \mathbf{L} - \varphi(\mathbf{X}_0).$$

Unknown parameters in `gama-local` mathematical model are points coordinates and orientation angles (transforming observed directions to bearings). The observables described by functions (12) belong into two classes

**linear observables:** horizontal and slope distances, height differences, control coordinates and vectors (coordinate differences),

**angular observables:** directions, horizontal and zenith angles.

Internally in `gama-local` unknown corrections to linear observables are computed in millimeters and corrections to angular observables in centigrade seconds. To reflect the internal units in used all partial derivatives of angular observables by coordinates are scaled by factor  $2000/\pi = 10^{-3} \times (200 \times 10^4/\pi)$ .

When computing coefficients of project equations (1) we expect that approximate coordinates of points are known with sufficient accuracy needed for linearization of generally nonlinear relations between observations and unknown parameters. Most often this is true but not always and generally we have to check how close our approximation is to adjusted parameters.

Generally we check linearization in adjustment by double calculation of residuals

$$\mathbf{v}^i = \mathbf{A}\mathbf{x} - \mathbf{b},$$

$$\mathbf{v}^{ii} = \bar{\ell}(\bar{\mathbf{x}}) - \ell,$$

where in our notation  $\mathbf{x}$  is vector of corrections of approximate unknown parameters  $\mathbf{x}_0$ ,  $\mathbf{b}$  vector of reduced observations,  $\ell$  vector of observations and  $\bar{\ell}(\bar{\mathbf{x}})$  is vector of adjusted observations computed from adjusted coordinates  $\bar{\mathbf{x}} = \mathbf{x}_0 + \mathbf{x}$ . Disagreement  $\mathbf{v}^i \neq \mathbf{v}^{ii}$  signals discrepancies in linearization.

Program `gama-local` similarly computes and tests differences in values of adjusted observations once computed from residuals and once from adjusted coordinates. For measured directions and angles `gama-local` computes in addition transverse deviation corresponding to computed angle difference in the distance of target point (or the farther of two targets for angle). As a criterion of bad linearization is supposed positional deviation greater or equal to 0.0005 millimetres.

## Example

```
Test of linearization error
*****
```

```
Diffs in adj. obs from residuals and from adjusted coordinates
*****
```

i	standpoint	target	observed	r	difference	
				hodnota = [mm cc] = [cc] == [mm]=		
2	3022184030	3022724008 dist.	28.39200	-7.070		-0.003
3		3022724002 dist.	72.30700	-18.815		-0.001
7		3000001063 dir.	286.305200	11.272	-0.002	-0.001
8		3022724008 dir.	357.800600	-23.947	0.037	0.002

From the practical point of view it might seem that the tolerance 0.0005 mm for detecting poor linearization is too strict. Its exceeding in program `gama-local` results in repeated adjustment with substitute adjusted coordinates for approximate. Given tolerance was chosen so strict to guarantee that listed output results would never be influenced by linearization and could serve for verification and testing of numerical solutions produced by other programs.

Implicitly coordinates of constrained points are not changed in iterative adjustments. This feature can be changed in XML input data by setting `<parameters update-constrained-coordinates = "yes" />` (see [Section 2.5 \[Network parameters\], page 9](#)).

Iterated adjustment with successive improvement of approximate coordinates converges usually even for gross errors in initial estimates of unknown coordinates. If the influence of linearization is detected after adjustment, quite often only one iteration is sufficient for recovering.

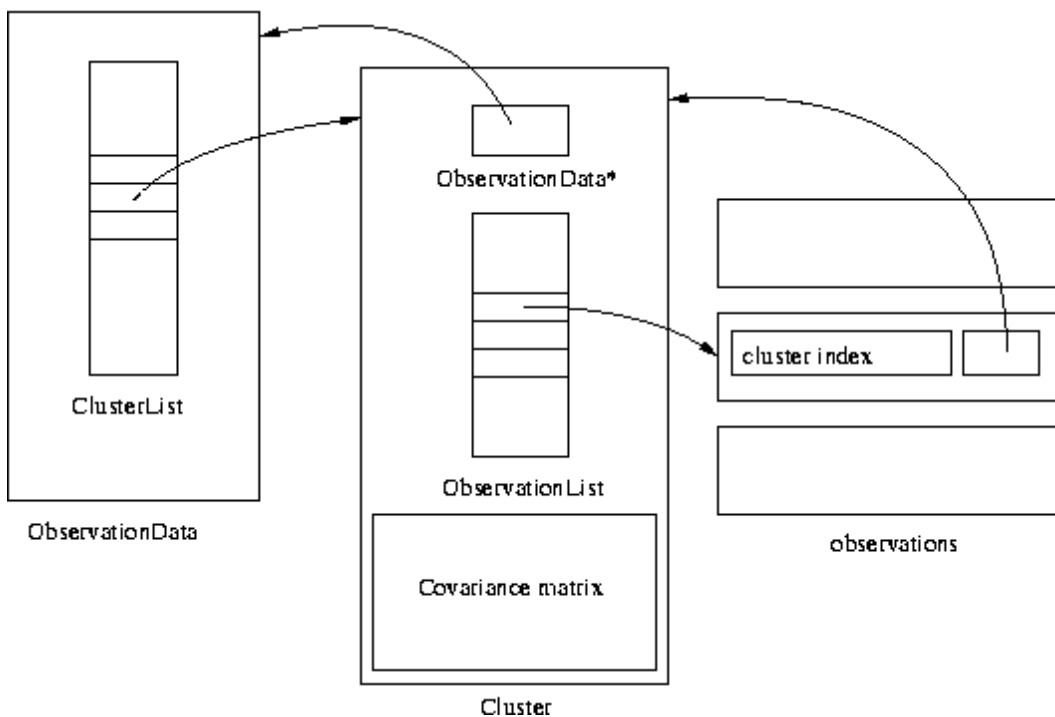
For any automatically controlled iteration we have to set up certain stopping criterion independent on the convergence and results obtained. Program `gama-local` computes

iterated adjustment three times at maximum. If the bad linearization is detected even after three readjustments it signals that given network configuration is somehow suspicious.

## 4 Data structures and algorithms

### 4.1 Observation data and points

The Gama observation data structures are designed to enable adjustment of any combination of possibly correlated observations. At its very early stage Gama was limited to adjustment of uncorrelated observations. Only directions and distances were available and observable's weight was stored together with the observed value in a single object. A single array of pointers to observation objects was sufficient for handling all observations. So called *orientation shifts* corresponding to directions measured from a point were stored together with coordinations in *point objects*.



To enable adjustment of possibly correlated observations (like angles derived from observed directions or already adjusted coordinates from a previous adjustment) Gama has come with the concept of *clusters*. Cluster is an object with a common variance-covariance matrix and a list of pointers to observation objects (distances, directions, angles, etc.). Weights were removed from observation objects and replaced with a pointer to the cluster to which the observation belong. All clusters are joined in a common object **ObservationData**; similarly to observations, each cluster contains a pointer to its parent **Observation Data** object. *Orientation shifts* were separated from coordinates and are stored in the cluster containing the bunch of directions and thus number of orientations is not limited to one for a point.

This organisation of observational information has proved to be effective. Template classes **ObservationData** and **Cluster** are used as base classes both in **gama-local** and **gama-w3**

```
template <typename Observation>
class ObservationData
```

```

{
public:
    ClusterList<Observation> CL;

    ObservationData();
    ObservationData(const ObservationData& cod);
    ~ObservationData();

    ObservationData& operator=(const ObservationData& cod);
    template <typename P> void for_each(const P& p) const;
};

template <typename Observation>
class Cluster
{
public:
    const ObservationData<Observation>*    observation_data;
    ObservationList<Observation>            observation_list;
    typename Observation::CovarianceMatrix  covariance_matrix;

    Cluster(const ObservationData<Observation>* od);
    virtual ~Cluster();

    virtual Cluster* clone(const ObservationData<Observation>*) const = 0;
    double stdDev(int i) const;
    int size() const;
    void update();
    int activeCount() const;
    typename Observation::CovarianceMatrix activeCov() const;
};

```

The following template class `PointBase` for handling point information is used in `gama-w3`. The template class `PointBase` relies internally on `std::map` container but comes with its own interface (in `gama-local` `std::map` was used directly for storing points).

```

template <typename Point>
class PointBase
{
    typedef std::map<typename Point::Name, Point*> Points;

public:
    PointBase();
    PointBase(const PointBase& cod);
    ~PointBase();

    PointBase& operator=(const PointBase& cod);
    void put(const Point&);

```

```

void put(Point*);
Point*      find(const typename Point::Name&);
const Point* find(const typename Point::Name&) const;
void erase(const typename Point::Name&);
void erase();

class const_iterator;
const_iterator begin();
const_iterator end ();

class iterator;
iterator begin();
iterator end ();
};

```

Template classes `ObservationData` and `PointBase` are defined in namespace `GNU_gama` and are located in the source directory `gnu_gama`.

## 4.2 Supported ellipsoids

id	a	b, 1/f, f	description	
airy	6377563.396	6356256.910	Airy ellipsoid 1830	[4]
airy_mod	6377340.189	6356034.446	Modified Airy	[4]
apl1965	6378137	298.25	Appl. Physics. 1965	[4]
andreae1876	6377104.43	300.0	Andrae 1876 (Denmark, Iceland)	[4]
australian	6378160	298.25	Australian National 1965	[3]
bessel	6377397.15508	6356078.96290	Bessel ellipsoid 1841	[1]
bessel_nam	6377483.865	299.1528128	Bessel 1841 (Namibia)	[4]
clarke1858a	6378361	6356685	Clarke ellipsoid 1858 1st	[3]
clarke1858b	6378558	6355810	Clarke ellipsoid 1858 2nd	[3]
clarke1866	6378206.4	6356583.8	Clarke ellipsoid 1866	[3]
clarke1880	6378316	6356582	Clarke ellipsoid 1880	[3]
clarke1880m	6378249.145	293.4663	Clarke ellipsoid 1880 (modified)	[4]
cpm1799	6375738.7	334.29	Comm. des Poids et Mesures 1799	[4]
delambre	6376428	311.5	Delambre 1810 (Belgium)	[4]
engelis	6378136.05	298.2566	Engelis 1985	[4]
everest1830	6377276.345	300.8017	Everest 1830	[4]
everest1848	6377304.063	300.8017	Everest 1948	[4]
everest1856	6377301.243	300.8017	Everest 1956	[4]
everest1869	6377295.664	300.8017	Everest 1969	[4]

everest_ss	6377298.556	300.8017	Everest (Sabah and Sarawak)	[4]
fisher1960	6378166	298.3	Fisher 1960 (Mercury Datum)	[3] [4]
fisher1960m	6378155	298.3	Modified Fisher 1960	[3] [4]
fischer1968	6378150	298.3	Fischer 1968	[4]
grs67	6378160	298.2471674270	GRS 67 (IUGG 1967)	[4]
grs80	6378137	298.257222101	Geodetic Reference System 1980	[1]
hayford	6378388	297	Hayford 1909 (International)	[1] [3]
helmert	6378200	298.3	Helmert ellipsoid 1906	[3]
hough	6378270	297	Hough	[4]
iau76	6378140	298.257	IAU 1976	[4]
international	6378388	297	International 1924 (Hayford 1909)	[1] [3]
kaula	6378163	298.24	Kaula 1961	[4]
krassovski	6378245	298.3	Krassovski ellipsoid 1940	[1]
lerch	6378139	298.257	Lerch 1979	[4]
mprts	6397300	191.0	Maupertius 1738	[4]
mercury	6378166	298.3	Mercury spheroid 1960	[3]
merit	6378137	298.257	MERIT 1983	[4]
new_intl	6378157.5	6356772.2	New International 1967	[4]
nwl1965	6378145	298.25	Naval Weapons Lab., 1965	[4]
plessis	6376523	6355863	Plessis 1817 (France)	[4]
se_asia	6378155	6356773.3205	Southeast Asia	[4]
sgs85	6378136	298.257	Soviet Geodetic System 85	[4]
schott	6378157	304.5	Schott 1900 spheroid	[3]
sa1969	6378160	298.25	South American Spheroid 1969	[3]
walbeck	6376896	6355834.8467	Walbeck	[4]
wgs60	6378165	298.3	WGS 60	[4]
wgs66	6378145	298.25	WGS 66	[4]
wgs72	6378135	298.26	WGS 72	[4]
wgs84	6378137	298.257223563	World Geodetic System 1984	[1]

[1] Milos Cimbalnik - Leos Mervart: Vyssi geodezie 1, 1997, Vydavatelstvi CVUT, Praha

[2] Milos Cimbalnik: Derived Geometrical Constants of the Geodetic Reference System 1980, Studia geoph. et geod. 35 (1991), pp. 133-144, NCSAV, Praha

- [3] Glossary of the Mapping Sciences, Prepared by a Joint Committee of the American Society of Civil Engineers, American Congress on Surveying and Mapping and American Society for Photogrammetry and Remote Sensing (1994), USA, ISBN 1-57083-011-8, ISBN 0-7844-0050-4
- [4] Gerald Evenden: proj - forward cartographic projection filter (rel. 4.3.3), <http://www.remotesensing.org/proj>

### 4.3 Transformation from spatial to geographical coordinates

Spatial coordinates  $(X, Y, Z)$  can be easily computed from geographical ellipsoidal coordinates  $(B, L, H)$ , where  $B$  is geographical latitude,  $L$  geographical longitude and  $H$  is ellipsoidal height, as

$$\begin{pmatrix} X \\ Y \\ Z \end{pmatrix} = \begin{pmatrix} (N + H) \cos B \cos L \\ (N + H) \cos B \sin L \\ (N(1 - e^2) + H) \sin B \end{pmatrix}$$

where  $N = a/\sqrt{1 - e^2 \sin^2 B}$  is the radius of curvature in the prime vertical,  $e^2 = (a^2 - b^2)/a^2$  is the first eccentricity for the given rotational ellipsoid (spheroid) with semi-major axis  $a$  and semi-minor axis  $b$ .

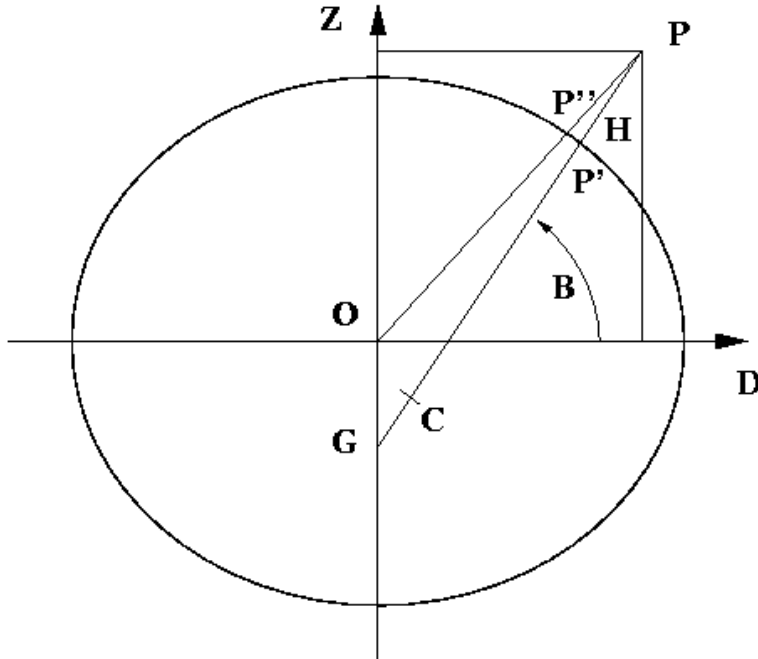
In the case of coordinate transformation from  $(X, Y, Z)$  to  $(B, L, H)$ , the longitude is given by the formula

$$\tan L = Y/X.$$

Now we can introduce  $D = \sqrt{X^2 + Y^2}$ , so that the cartesian system become  $(D, Z)$ . Coordinates  $B$  and  $H$  are then usually computed by iteration with some starting value of  $B_0$ , for example  $\tan B_0 = Z/D/(1 - e^2)$ ,

$$\tan B_i = Z/D + \frac{N_{i-1}}{(N_{i-1} + H_{i-1})} e^2 \tan B_{i-1}, \quad H_i = D/\cos B_{i-1} = Z/\sin B_{i-1} - N(1 - e^2)$$

B. R. Bowring described a closed formula<sup>1</sup> that is more effective and sufficiently accurate and that is used in GNU Gama.



The centre of curvature  $C$  of the spheroid corresponding to  $P'$  is the point

$$(e^2 a \cos^2 u, -e'^2 b \sin^3 u),$$

where  $e'^2 = (a^2 - b^2)/b^2$  is second eccentricity and  $u$  is the parametric latitude of the point  $P'$ ,  $(1 - e^2)N \sin B = b \sin u$ . Therefore

$$\tan B = \frac{Z + e'^2 b \sin^3 u}{D - e^2 a \cos^3 u}.$$

This is clearly an iterative solution; but it has been found that this formula is extremely accurate using the single first approximation for  $u$  for the  $\tan u = (Z/D)(a/b)$ . Maximum error in earth bound region is  $3e-8$  of sexadecimal arc seconds ( $5e-7$  millimetres); maximum is  $0.0018''$  (0.1 millimetres) at height  $H = 2a$ .

#### 4.4 Class `g3::Model`

`g3::model` documentation shall come here ...

```
namespace GNU_gama { namespace g3 {
```

```
    class Model {
```

<sup>1</sup> B. R. Bowring: Transformation from spatial to geographical coordinates, Survey Review XXIII, 181, July 1976

```
public:

    typedef GNU_gama::PointBase<g3::Point>          PointBase;
    typedef GNU_gama::ObservationData<g3::Observation> ObservationData;

    PointBase          *points;
    ObservationData    *obs;

    GNU_gama::Ellipsoid ellipsoid;

    Model();
    ~Model();

    Point* get_point(const Point::Name&);
    void  write_xml(std::ostream& out) const;
    void  pre_linearization();
}}}
```



# Appendix A Copying This Manual

## A.1 GNU Free Documentation License

Version 1.1, March 2000

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## Concept Index

### <

<angle />.....	13
<coordinates>.....	16
<description>.....	9
<direction />.....	12
<distance />.....	13
<gama-local>.....	8
<height-differences>.....	15
<network>.....	8
<obs>.....	11
<parameters />.....	9
<point />.....	10
<points-observations>.....	9
<s-distance />.....	14
<vectors>.....	16
<z-angle />.....	14

### A

absolute terms.....	23
analysis, statistical.....	24
angle.....	13
angle, zenith.....	14

### C

contributors.....	5
coordinate differences.....	16
coordinates, observed.....	16

### D

description, network.....	9
deviation, reference standard.....	25
deviation, standard.....	25
difference, height.....	15
direction.....	12
distance, horizontal.....	13
distance, slope.....	14
download.....	2

### F

FDL, GNU Free Documentation License.....	43
--	----

### G

gama-local.....	2
gross absolute terms.....	23

### H

height differences.....	15
height, difference.....	15
horizontal distance.....	13
horizontal, distance.....	13

### I

information on points.....	26
install.....	2

### N

network description.....	9
network parameters.....	9

### O

observations, Points.....	9
observations, set.....	11
observed coordinates.....	16
observed, coordinates.....	16

### P

parameters of statistical analysis.....	24
parameters, network.....	9
point.....	10
points.....	26
points and observations.....	9
points, observations.....	9
prolog.....	7

### R

reductions, horizontal and zenith angles.....	4
reference standard deviation.....	25
Reporting bugs.....	5

### S

set of observations.....	11
set, observations.....	11
slope distance.....	14
slope, distance.....	14
standard deviation.....	25
statistical analysis.....	24

### T

terms, absolute.....	23
test on the reference standard deviation.....	25

### V

vector.....	16
-------------	----

### Z

zenith angle.....	14
zenith, angle.....	14