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gamit is not an incremental improvement on the strava rtk t+s. however, even though it is not an improvement on the precise rtk t+s, it can still meet the requirement for large-scale monitoring of the real-time precise monitoring of the gnss network. it is expected to take full advantage of the waveform of global navigation satellite system with its precise phase on the basis of the existing calculation algorithm, and also established a new category of high-accuracy differential gps precise differential capability. the main modifications on the basis of the strava rtk t+s software are as follows: the core of the gamit processing is the correction of errors, which calculates the differential correction of the precise rtk tracking and corrects the internal systematic error. it is divided into the global block and the local block. the global block includes differential velocity, differential position, and geopotential model corrections. the local block provides differential troposphere, ionosphere, and satellite clock corrections. generally, the whole correction procedure is completed within 30s. the software is an open-source modeling application which can be used free of charge by anyone. current versions of the software are "gamit 3.12.6" and "gamit 10.0.1". bernese gps all-in-one gnss precise positioning software system is a novel type of software model based on precise rtk tracking mode and precise gnss differential mode. the main feature of the system is to use the precise gnss differential mode to extend the positioning accuracy of gps, so as to improve the stability and accuracy of position. the precise gnss differential mode is based on correction of system errors. it was first proposed by murray [1] in 1995, and then corrected based on position, the velocity, the ionosphere and other factors, in order to correct the differential errors of gnss, so as to improve the stability and accuracy of position.



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