



# RadarFX

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## Users Guide





# RadarFX

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## Users Guide

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# Preface

This manual is for persons who will install RadarFX and use it to view simulations. The manual assumes that you are familiar with basic administrative tasks and the graphical window environment for your operating system.

For the latest product information, please see release-specific documentation for your version of RadarFX.

## ***MÄK Products***

RadarFX is a member of the VT MÄK line of software products designed to streamline the process of developing and using networked simulated environments. The VT MÄK product line includes the following:

- ♦ VR-Link® Network Toolkit. VR-Link is an object-oriented library of C++ functions and definitions that implement the High Level Architecture (HLA) and the Distributed Interactive Simulation (DIS) protocol. VR-Link has built-in support for the RPR FOM and allows you to map to other FOMs. This library minimizes the time and effort required to build and maintain new HLA or DIS-compliant applications, and to integrate such compliance into existing applications.

VR-Link includes a set of sample debugging applications and their source code. The source code serves as an example of how to use the VR-Link Toolkit to write applications. The executables provide valuable debugging services such as generating a predictable stream of HLA or DIS messages, and displaying the contents of messages transmitted on the network.

- ♦ MÄK RTI. An RTI (Run-Time Infrastructure) is required to run applications using the High Level Architecture (HLA). The MÄK RTI is optimized for high performance. It has an API, RTIspy®, that allows you to extend the RTI using plug-in modules. It also has a graphical user interface (the RTI Assistant) that helps users with configuration tasks and managing federates and federations.

- ♦ VR-Forces®. VR-Forces is a computer generated forces application and toolkit. It provides an application with a GUI, that gives you a 2D and 3D views of a simulated environment.

You can create and view entities, aggregate them into hierarchical units, assign tasks, set state parameters, and create plans that have tasks, set statements, and conditional statements. You can simulate using entity-level modeling, which focuses on the actions of individual people and vehicles, and aggregate-level modeling, which focuses on the interaction of large hierarchical units.

VR-Forces also functions as a plan view display for viewing remote simulation objects taking part in an exercise. Using the toolkit, you can extend the VR-Forces application or create your own application for use with another user interface.

- ♦ VR-Vantage™. VR-Vantage is a line of products designed to meet your simulation visualization needs. It includes three end-user applications (VR-Vantage Stealth, VR-Vantage PVD, and VR-Vantage IG) and the VR-Vantage Toolkit.
  - VR-Vantage Stealth displays a realistic, 3D view of your virtual world, a 2D plan view, and an exaggerated reality (XR) view. Together these views provide both situational awareness and the big picture of the simulated world. You can move your viewpoint to any location in the 3D world and can attach it to simulation objects so that it moves as they do.
  - VR-Vantage IG is a configurable desktop image generator (IG) for out the window (OTW) scenes and remote camera views. It has most of the features of the Stealth, but is optimized for its IG function.
  - VR-Vantage PVD provides a 2D plan view display. It gives you the big picture of the simulated world.
  - SensorFX. SensorFX is an enhanced version of VR-Vantage that uses physics based sensors to view terrain and simulation object models that have been materially classified. It is built in partnership with JRM Technologies.
  - The VR-Vantage Toolkit is a 3D visual application development toolkit. Use it to customize or extend MÄK's VR-Vantage applications, or to integrate VR-Vantage capabilities into your custom applications. VR-Vantage is built on top of OpenSceneGraph (OSG). The toolkit includes the OSG version used to build VR-Vantage.
- ♦ MÄK Data Logger. The Data Logger, also called the Logger, can record HLA and DIS exercises and play them back for after-action review. You can play a recorded file at speeds above or below normal and can quickly jump to areas of interest. The Logger has a GUI and a text interface. The Logger API allows you to extend the Logger using plug-in modules or embed the Logger into your own application. The Logger editing features let you merge, trim, and offset Logger recordings.
- ♦ VR-Exchange™. VR-Exchange allows simulations that use incompatible communications protocols to interoperate. For example, within the HLA world, using VR-Exchange, federations using the HLA RPR FOM 1.0 can interoperate with simulations using RPR FOM 2.0, or federations using different RTIs can interoperate. VR-Exchange supports HLA, TENA, and DIS translation.



- ♦ VR-TheWorld™ Server. VR-TheWorld Server is a simple, yet powerful, web-based streaming terrain server, developed in conjunction with Pelican Mapping. Delivered with a global base map, you can also easily populate it with your own custom source data through a web-based interface. The server can be deployed on private, classified networks to provide streaming terrain data to a variety of simulation and visualization applications behind your firewall.
- ♦ DI-Guy™. The DI-Guy product line is a set of software tools for real-time human visualization, simulation, and artificial intelligence. Every DI-Guy software offering comes with thousands of ready-to-use characters, appearances, and motions. DI-Guy enables the easy creation of crowds and individuals who are terrain aware, autonomous, and react intelligently to ongoing events. Save time, money and create outstanding simulations with DI-Guy. The DI-Guy product line includes the following products:
  - The DI-Guy SDK. Embed the DI-Guy library in your real-time application and populate your world with lifelike human characters.
  - DI-Guy Scenario™. Author and visualize human performances in a rich, user-friendly graphical environment. Use DI-Guy Scenario as an end visualization application or save scenarios and load them into your DI-Guy SDK enabled application.
  - ECOSim. Enhanced Company Operations Simulation (ECOSim) is a company-level training simulation that teaches leaders how best to deploy troops, UAVs, convoys, and other assets. ECOSim focuses on ease-of-use, rapid scenario generation, runtime operator control, and realistic and reactive human simulation.
  - DI-Guy AI. Generate crowds of autonomous characters to quickly populate your worlds with hundreds and thousands of terrain-aware, collision avoiding DI-Guys. Used as a module on top of DI-Guy Scenario and DI-Guy SDK.
  - Expressive Faces Module. Enable DI-Guy characters to have faces that display emotion, eyes that look in directions and blink, and lips that sync to sound files.
  - DI-Guy Motion Editor. Create or customize motions to your particular needs in an easy-to-use graphical application.
- ♦ RadarFX. RadarFX is a client-server application that simulates synthetic-aperture radar (SAR). The server application, which is based on VR-Vantage and SensorFX, loads a terrain database and, optionally, connects to simulations. A client application requests SAR images from the server. RadarFX includes a sample client application.

## ***How to Contact Us***

For RadarFX technical support, information about upgrades, and information about other MÄK products, you can contact us in the following ways:

### **Telephone**

|                    |        |                                        |
|--------------------|--------|----------------------------------------|
| Call or fax us at: | Voice: | 617-876-8085 (extension 3 for support) |
|                    | Fax:   | 617-876-9208                           |

### **E-mail**

|                                |                                                      |
|--------------------------------|------------------------------------------------------|
| Sales and upgrade information: | <a href="mailto:info@mak.com">info@mak.com</a>       |
| Technical support:             | <a href="mailto:support@mak.com">support@mak.com</a> |

### **Internet**

|                                           |                                                                                                          |
|-------------------------------------------|----------------------------------------------------------------------------------------------------------|
| MÄK web site home page:                   | <a href="http://www.mak.com">www.mak.com</a>                                                             |
| License key requests:                     | <a href="http://www.mak.com/support/licenses/get-licenses">www.mak.com/support/licenses/get-licenses</a> |
| Product version and platform information: | <a href="http://www.mak.com/support/product-versions">www.mak.com/support/product-versions</a>           |
| For the free, unlicensed MÄK RTI:         | <a href="http://www.mak.com/resources/bonus-material">www.mak.com/resources/bonus-material</a>           |
| MÄK Community Forum:                      | <a href="http://www.mak.com/connect/forum">www.mak.com/connect/forum</a>                                 |

### **Post**

|                                |                                                                           |
|--------------------------------|---------------------------------------------------------------------------|
| Send postal correspondence to: | VT MÄK<br>150 Cambridge Park Drive, 3rd Floor<br>Cambridge, MA, USA 02140 |
|--------------------------------|---------------------------------------------------------------------------|

When requesting support, please tell us the product you are using, the version, and the platform on which you are running.

## Document Conventions

This manual uses the following typographic conventions:

|                                                                                     |                                                                                                                                                                                                                                  |
|-------------------------------------------------------------------------------------|----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Monospaced                                                                          | Indicates commands or values you enter.                                                                                                                                                                                          |
| <b>Monospaced Bold</b>                                                              | Indicates a key on the keyboard.                                                                                                                                                                                                 |
| Monospaced Italic                                                                   | Indicates command variables that you replace with appropriate values.                                                                                                                                                            |
| Blue text                                                                           | A hypertext link to another location in this manual or another manual in the documentation set.                                                                                                                                  |
| { }                                                                                 | Indicates required arguments.                                                                                                                                                                                                    |
| [ ]                                                                                 | Indicates optional arguments.                                                                                                                                                                                                    |
|                                                                                     | Separates options in a command where only one option may be chosen at a time.                                                                                                                                                    |
| (   )                                                                               | In command syntax, indicates equivalent alternatives for a command-line option, for example, (-h   --help).                                                                                                                      |
| /                                                                                   | Indicates a directory. Since MÄK products run on both Linux and Windows PC platforms, we use the / (slash) for generic discussions of pathnames. If you are running on a PC, substitute a \ (backslash) when you type pathnames. |
| <i>Italic</i>                                                                       | Indicates a file name, pathname, or a class name.                                                                                                                                                                                |
| sans Serif                                                                          | Indicates a parameter or argument.                                                                                                                                                                                               |
| ➤                                                                                   | Indicates a one-step procedure.                                                                                                                                                                                                  |
| <b>Menu → Option</b>                                                                | Indicates a menu choice. For example, an instruction to select the Save option from the File menu appears as:<br>Choose <b>File</b> → <b>Save</b> .                                                                              |
|  | Click the icon to run a tutorial video in the default browser.                                                                                                                                                                   |
|  | Indicates supplemental or clarifying information.                                                                                                                                                                                |
|  | Indicates additional information that you must observe to ensure the success of a procedure or other task.                                                                                                                       |

Directory names are preceded with dot and slash characters that show their position with respect to the RadarFX home directory. For example, the directory *vrvan-tagex.x1.1/doc* appears in the text as *./doc*.

## **Mouse Button Naming Conventions**

An instruction to click the mouse button, refers to clicking the primary mouse button, usually the left button for right-handed mice and the right button for left-handed mice. The context-sensitive menu, also called a popup menu or right-click menu, refers to the menu displayed when you click the secondary mouse button, usually the right button on right-handed mice and the left button on left-handed mice.

## ***Third Party Licenses***

MÄK software products may use code from third parties. This section contains the license documentation required by these third parties.

### **Boost License**

VR-Link, and all MÄK software that uses VR-Link uses some code that is distributed under the Boost License. All header files that contain Boost code are properly attributed. The Boost web site is: [www.boost.org](http://www.boost.org).

Boost Software License - Version 1.0 - August 17th, 2003

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## **libXML and libICONV**

VR-Link and all MÄK software that uses VR-Link, links in libXML and libICONV. On some platforms the compiled libraries and header files are distributed with MÄK Products. MÄK has made no modifications to these libraries. For more information about these libraries please see the following web sites:

- ♦ The LGPL license is available at: <http://www.gnu.org/licenses/lgpl.html>.
- ♦ Information about IconV is at: <http://www.gnu.org/software/libiconv/>.
- ♦ Information about LibXML is at: <http://xmlsoft.org/>.





# 1. Introduction to RadarFX

This chapter provides a brief introduction to RadarFX and explains how to install it. You must also install the MÄK license manager. To use RadarFX with HLA, you must install an RTI.

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## **1.1. Introduction to RadarFX**

RadarFX (RadarFX) is a client-server application that can simulate synthetic-aperture radar (SAR). The server application, which is based on VR-Vantage and SensorFX, loads a terrain database and, optionally, connects to simulations. A client application requests SAR images from the server. RadarFX includes a sample client application.

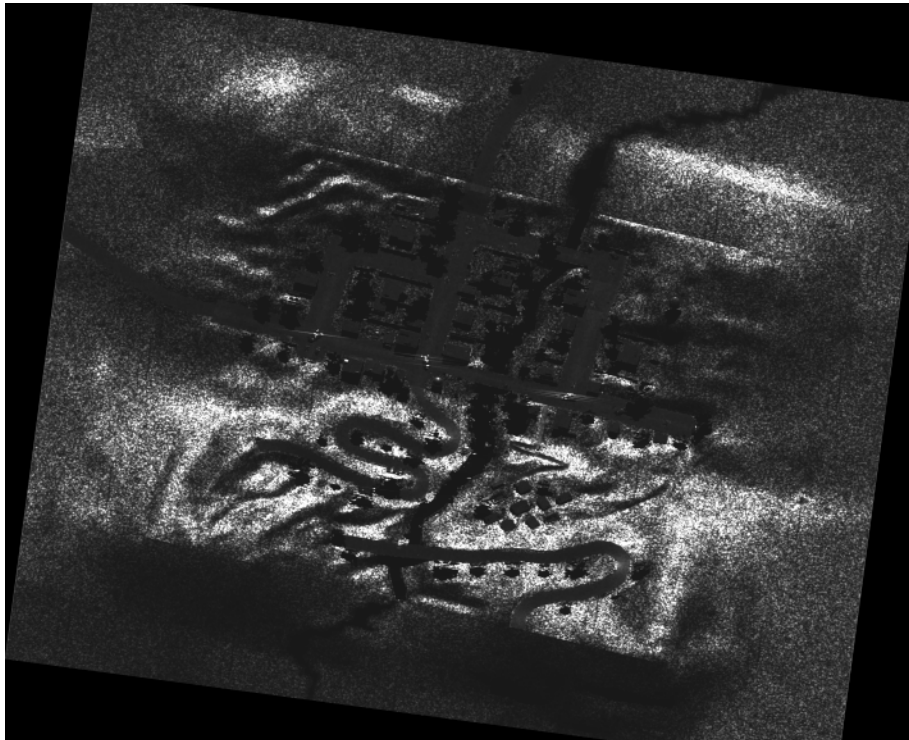


Figure 1-1. RadarFX image



RadarFX includes the documentation for VR-Vantage and SensorFX, which completely explain how to use those products. This manual provides only enough information about those applications to allow you to use RadarFX.

---



## 1.2. Installing RadarFX

A full RadarFX installation includes three components: the application, the License Manager software, and for HLA operation, an RTI (or Runtime Infrastructure.)

Before you install RadarFX, please read the Release Notes to see if there are any special instructions for installation.

Note the following:

- ♦ You must have administrator privileges to install MÄK products on Windows Vista.
- ♦ When you install large applications on Windows Vista or later, there may be a delay of up to several minutes from the time you try to run the setup program to the time that an installation dialog box is displayed. This delay can also take place between the time that RadarFX unpacks compressed data files and the time the data installer starts. This is due to how Windows scans setup programs before it executes them. If you experience this problem, turning off User Access Control can reduce or eliminate this delay.

RadarFX is provided as executable installer files on DVD, or as downloaded files. The installers are named to indicate the compiler used to build that version of RadarFX.

- To install RadarFX, run the application installer. Then, run the data installer. Follow the instructions in the installation wizard. (You must run the application installer and the data installer.)

### 1.2.1. Uninstalling RadarFX

Because installation of RadarFX is a two step process, uninstallation is also a two-step process.

**To uninstall RadarFX:**

1. In the RadarFX root directory, run *unins001.exe*.
2. In the RadarFX root directory, run *unins000.exe*.

### 1.3. The RadarFX Directory Structure

The installation process creates the RadarFX directory tree shown in [Figure 1-2](#) (runtime and toolkit).

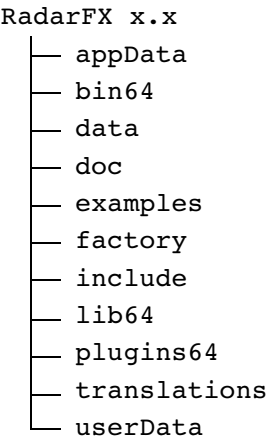


Figure 1-2. RadarFX directory structure

[Table 1-1](#) describes the contents of the directories.

Table 1-1: Contents of RadarFX directories

| Directory             | Directory contents                                                                                              |
|-----------------------|-----------------------------------------------------------------------------------------------------------------|
| <i>./appData</i>      | Subdirectories contain data required by the RadarFX applications, such as model definitions and saved settings. |
| <i>./bin64</i>        | Executables and dynamic link libraries.                                                                         |
| <i>./data</i>         | Sample databases, images, and vehicle models.                                                                   |
| <i>./doc</i>          | RadarFX documentation and class reference files.                                                                |
| <i>./examples</i>     | Examples for the RadarFX Toolkit API.                                                                           |
| <i>./factory</i>      | Default settings (for reverting to “factory” settings).                                                         |
| <i>./include</i>      | Header files for the RadarFX Toolkit API.                                                                       |
| <i>./lib64</i>        | Libraries for building applications with the RadarFX Toolkit API.                                               |
| <i>./plugins64</i>    | Plug-in shared libraries.                                                                                       |
| <i>./translations</i> | Translation files for localizing RadarFX menus.                                                                 |
| <i>./userData</i>     | Terrain and scene files saved by application users.                                                             |

## **1.4. Installing and Setting Up the MÄK License Manager**

Before you can use a MÄK product, you must obtain a valid license file, install the MÄK License Manager, and configure the license server and client machines. The License Manager uses a client-server architecture, so you do not need to install the License Manager on every computer on which you install MÄK products. You only need to install it on the computer that you will use as the license server.



If you have already installed the License Manager for another MÄK product, you do not have to install it again. You just need to make sure you have licenses for your newly installed products.

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The License Manager installer is included on MÄK installation media. It is separate from the product installers. You can download the installers from our web site at <http://www.mak.com/license-support.html> or you can download directly from:

- ♦ Windows:  
<ftp://ftp.mak.com/out/MAKLicenseManager-win-setup.exe> (for 32-bit systems)  
<ftp://ftp.mak.com/out/MAKLicenseManager-win64-setup.exe>
- ♦ Linux:  
<ftp://ftp.mak.com/out/MAKLicenseManager-linux-setup.tar.gz> (for 32-bit systems)  
<ftp://ftp.mak.com/out/MAKLicenseManager-linux64-setup.tar.gz>

Complete installation and configuration instructions are included with the License Manager installer. Instructions are also available at the license support page.

Some customers use dongle licenses instead of running a license server. Instructions for using dongles are in the License Manager documentation.

### 1.4.1. Specifying the License Server

The first time you run a MÄK application on a particular computer, the License Setup dialog box opens (Figure 1-3). It prompts you to enter the hostname of the license server and optionally, a port number.

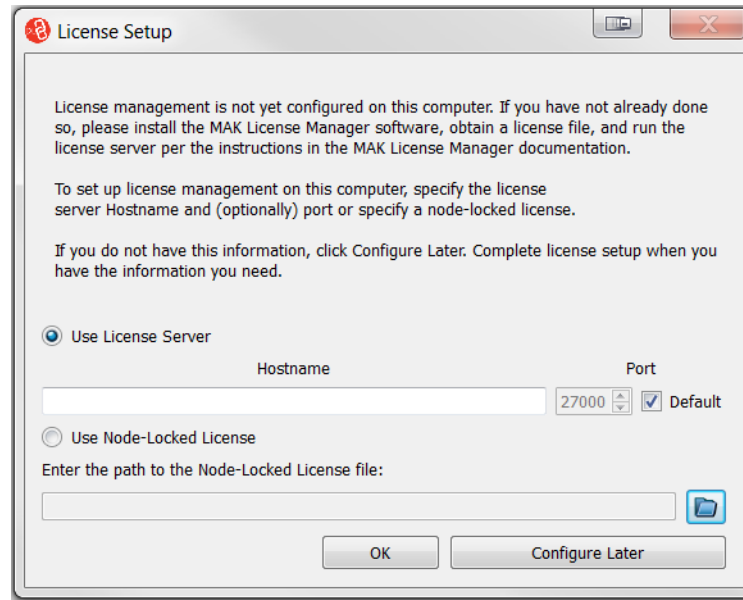


Figure 1-3. License Setup dialog box

If you do not know the hostname of the license server, click Configure Later. When you have the hostname, you can start the application again and complete the dialog box. You will not be able to run any MÄK applications until you set up license management.

If you know the hostname, type it in the Hostname box. Then click OK. The application will start.

Under limited circumstances, MÄK issues node-locked licenses. If you have a node locked license, select the Use Node Locked License option and enter the path to the license file.

#### The MAKLMGRD\_LICENSE\_FILE Environment Variable

As an alternative to using the License Setup procedure described in the previous section, you can configure the license server in an environment variable. The MAKLMGRD\_LICENSE\_FILE environment variable identifies the server machine. If you set this environment variable, it overrides the settings stored by the License Setup procedure.

The syntax for the environment variable is: `@Server_name`. For example, if the server machine is oak, set the environment variable to `@oak`.



- ♦ If you are running MAK products on the license server machine, it is also a client, so you must specify the license server on that machine too.
  - ♦ If you change the license server, the saved configuration will no longer be valid and the License Setup dialog box will open the next time you start a MAK application.
  - ♦ You can clear the saved license configuration by deleting the cache file. On Windows 7, it is `C:\Users\user_name\AppData\Roaming\MAK\licenses<n>.txt`. (The `AppData` directory is hidden by default.) On Linux, it is `.mak/license<n>.txt`. (There may be more than one cache file, for example, `licenses1.txt` and `licenses2.txt`.)
- 

The following sections explain how to set environment variables on the different platforms that MAK products run on.

**To add the MAKLMGRD\_LICENSE\_FILE:**

1. Open the Control Panel.
2. On Windows 7, click System and Security.
3. Click System.
4. In the sidebar menu, click the Advanced System Settings. The System Properties dialog box opens.
5. Click Environment Variables. The Environment Variables dialog box opens.
6. Click New. The New System Variable dialog box opens.
7. In the Variable Name field, enter `MAKLMGRD_LICENSE_FILE`.
8. In the Variable Value field, enter `@server_name`, where `server_name` is the name of the license server.
9. Click OK to back out of each dialog box and set the variable.



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Different versions of Windows have slightly different wording of the various Control Panel options.

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## 1.5. Installing an RTI

An RTI is a software library (and perhaps supporting executables) that implements an HLA Interface Specification. In HLA, applications exchange FOM data through RTI calls, which means that all HLA applications need to use an RTI.



---

Because of differences in the low-level network mechanisms used by different RTI implementations (which include, but are not limited to packet layout), applications that want to interoperate in the same federation execution must use the same RTI implementation.

---

Because RTIs are usually provided as dynamic libraries that implement a fixed API, a federation can often switch from one RTI implementation to another between runs (without even recompiling the applications), but during each run, all participants must agree on which RTI to use, much as they must also agree on which FOM to use.

For the most recent information about the RTI versions supported by MÄK products, please see the release notes for your MÄK application.

### 1.5.1. Installing the MÄK RTI

To install the MÄK RTI, follow the instructions in Chapter 2 of *MÄK RTI Users Guide*.

#### Configuring Your System to Use the MÄK RTI

The RTI dynamic libraries must be located somewhere on your dynamic library search path. The path is specified in the PATH environment variable. The path is indicated by an environment variable as follows:

- ♦ Linux — LD\_LIBRARY\_PATH.
- ♦ Windows — PATH.

The MÄK RTI needs to know where to find the following configuration files:

- ♦ The federation configuration file (*.fed*, *.fdd*, or *.xml*) for your federation execution (required).
- ♦ The RID file (*rid.mtl*) (optional).

Put the configuration files in the directory from which you are running, or set the environment variable RTI\_CONFIG to the directory that contains them.

## **Running Applications with the MÄK RTI**

### **To run a MÄK application with the MÄK RTI:**

1. Be sure the license server is running.
2. Start the application. The RTI Assistant will prompt you to choose an RTI configuration.
3. Choose a configuration. If necessary start the rtiexec.
4. Click Connect. The application should run.

In many cases, you do not need to run the rtiexec to use the MÄK RTI, however you can run the rtiexec if you want to. (It is required to use certain features of the MÄK RTI.) For more information, please see your RTI documentation.

## 1.6. Localizing the Graphical User Interface

You can localize your MÄK product's graphical user interface so that it uses languages other than English. Your product includes a file called *.translations/product\_untranslated.ts*, for example *logger\_untranslated.ts* or *vrforces\_untranslated.ts*. The file contains entries for all of the application-specific menu and dialog box text. The Qt Linguist tool, which is included with RadarFX, lets you map the English text provided by MÄK to your chosen language.

### To edit a resource file:

1. Start the Qt Linguist utility. It is *.translations/linguist.exe*
2. In the Qt Linguist window, choose **File** → **Open**. Select the file *.translations/product\_untranslated.ts*. The Settings for filename dialog box opens (Figure 1-4).

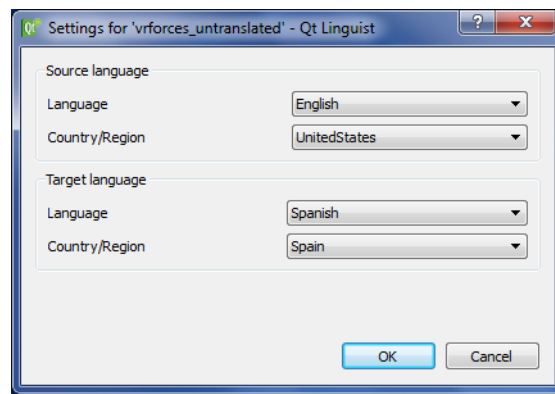


Figure 1-4. Linguist settings dialog box

3. Select values for the source language, target language, and target region or country.
4. Click OK. The translation file is opened and a list of classes is displayed on the left side of the window (Figure 1-5).



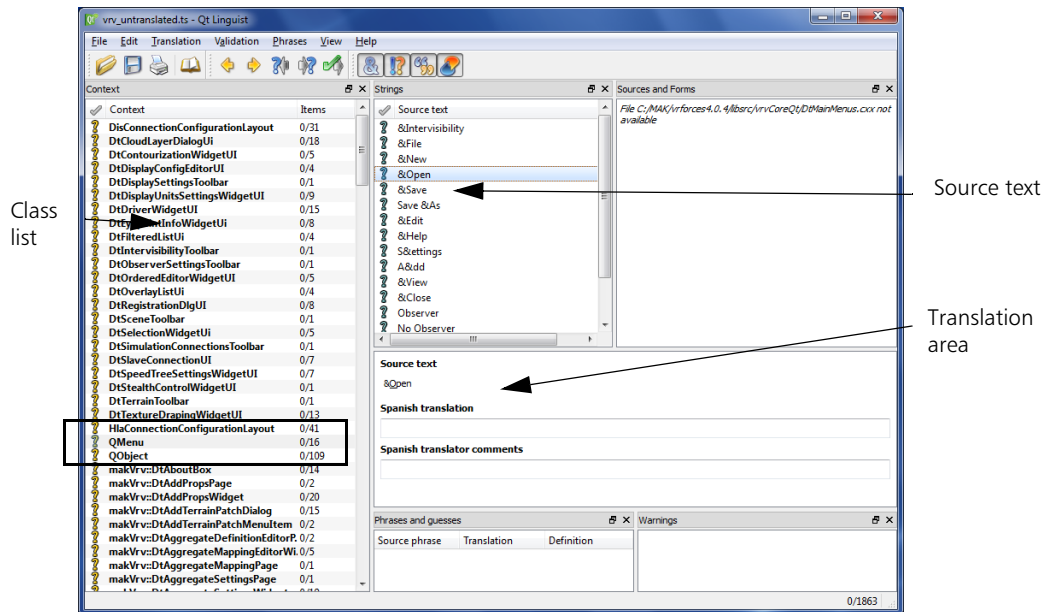


Figure 1-5. Linguist window

5. To translate text, you select each class in turn and translate the text associated with that class. You do not have to understand anything about what the classes mean, you just have to translate the text. In [Figure 1-5](#), *QMenu* is selected. The Strings window lists text that can be translated. Text that has not been translated has a question mark in the checkmark column.
6. In the Source Text list, select the word you want to translate. The text is displayed under Source Text in the translation area (the window below the source text list.) [Figure 1-6](#) shows the text Open selected.

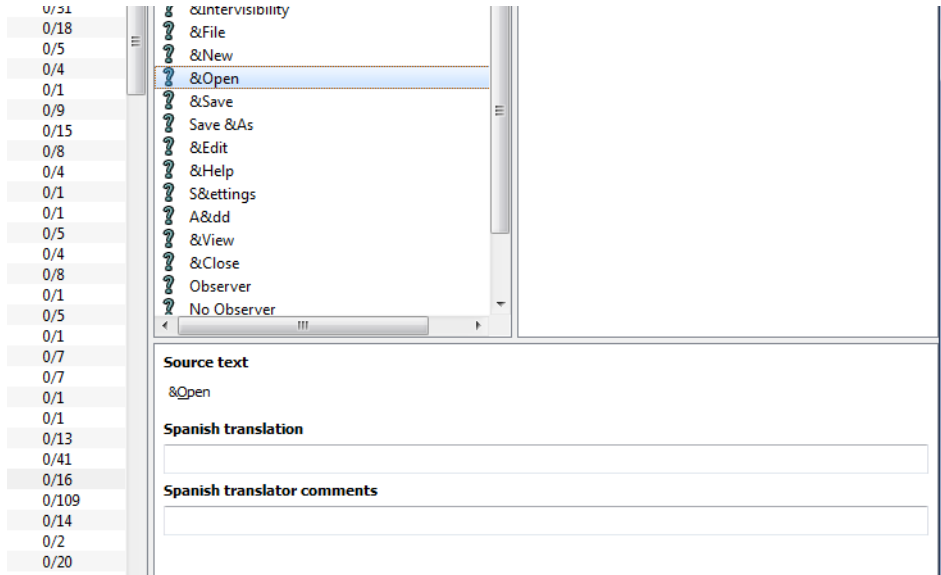


Figure 1-6. Text selected for translation

7. Place the cursor in the text box below *Language* Translation, where *Language* is the target language that you selected when you opened the translation file.
8. Type the translation text.
9. When you are done and you are certain of the translation, select the Done and Next button on the toolbar. A green check mark replaces the question mark (Figure 1-7). If you move to a different text string without clicking Done and Next, a yellow question mark is displayed for the string you translated. When you translate all elements for a class, a green check mark replaces the question mark next to the class name.

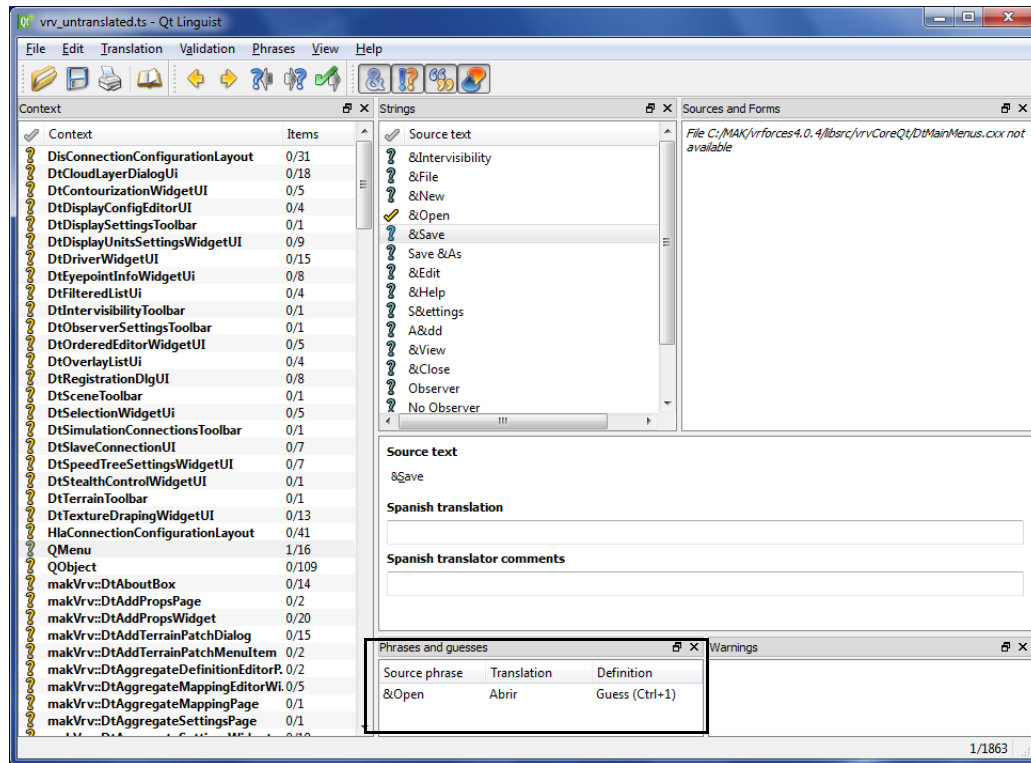


Figure 1-7. Completed translation for Open

10. Repeat this process for each element of source text for each class.
11. Choose **File** → **Release**. The file is saved in the format *filename.qm*.
12. Rename the file to a name that indicates the language to which you have translated the file, using the two-character abbreviation typically used with your language. For example, a Spanish translation would be renamed *product\_es.qm*.
13. Save your translated *.ts* file.

### 1.6.1. Translating Other Interface Files

The *product\_untranslated.ts* file contains all the text used in the RadarFX interface. However, there may be other text and messages that are not specific to RadarFX that are generated by the software that implements the RadarFX GUI. To translate this text, you need to translate the file *qt\_untranslated.ts*. Follow the same procedure as you did for *radarfx\_untranslated.ts*.

## **1.6.2. Applying the Language Files**

**To put the language file into effect, use one of the following methods:**

- ♦ Set your computer's environment to the proper language (LANG environment variable).
- ♦ Set the locale to the proper language.
- ♦ Start RadarFX with the `-G locale` command line option, where *locale* is the two-letter country code for the local language.



## 2. Using RadarFX Server

This chapter explains how to start and configure RadarFX.

|                                                  |     |
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| <a href="#">Opening a Terrain</a> .....          | 2-2 |
| <a href="#">Connecting to a Simulation</a> ..... | 2-3 |
| <a href="#">Configuring RadarFX Server</a> ..... | 2-3 |
| <a href="#">Configuring Sensors</a> .....        | 2-5 |

## 2.1. Starting RadarFX Server

To use RadarFX, you run the server and a client application. The client could be embedded in any third party application.

### To start RadarFX Server:

1. If you are using Windows 7, on the Start menu, choose **All Programs** → **MÄK Technologies** → **RadarFX 1.1** → **RadarFX Server**.

If you are using Windows 10, on the Start menu, choose **All apps** → **MÄK Technologies** → **RadarFX Server**.

RadarFX Server starts and the Load Terrain dialog box opens.

2. Select a terrain to load. RadarFX Server loads the terrain and displays it in the window (Figure 2-1).

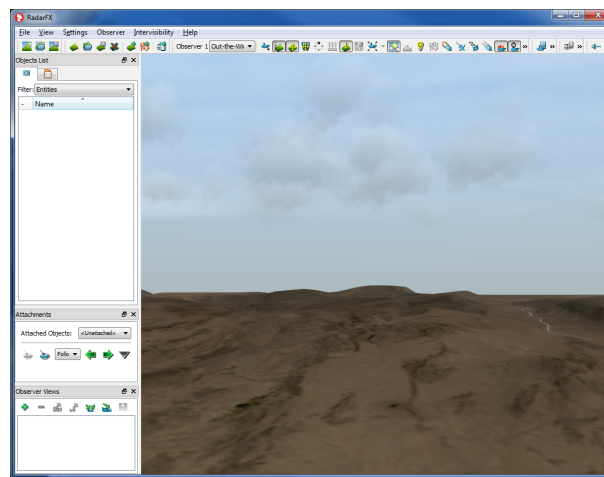


Figure 2-1. RadarFX Server



- ♦ Since RadarFX uses SensorFX, you will get best results with a terrain that has been materially classified for its use, or which supports material classification on demand. For details about material classification, please see *SensorFX Users Guide*. A materially classified terrain, *VR-VillageSensorFX.mtf* is included with RadarFX.
  - ♦ RadarFX does not support geocentric terrains if they are part of a terrain that does not include an osgEarth terrain patch.
-

## 2.2. Opening a Terrain

The previous section explained how to load a terrain from the Load Terrain dialog box when RadarFX starts up. However, if you choose not to load a terrain immediately, or want to load a different terrain at any time after startup, you can do so. For details, please see Section 3.3, “[Opening a Terrain](#),” in *VR-Vantage Users Guide*.

## 2.3. Connecting to a Simulation

You do not need to connect to a simulation to use a RadarFX client with the RadarFX server. However, if you do not connect to a simulation, you will not be able to view any entities in the server or use them as the viewpoint from which to capture an image.

To connect to a simulation, follow the instructions in Section 3.4, “[Connecting to a Simulation Network](#),” in *VR-Vantage Users Guide*.

## 2.4. Configuring RadarFX Server

You can configure:

- ♦ Server Listen Port. The port that the server is listening on for incoming connections from clients. Changing this value restarts the server immediately.
- ♦ Save Image Directory. The default directory to save images.
- ♦ Default Observer Mode Name. The default observer mode to use for image captures.
- ♦ Default Sensor Mode Name. The default sensor mode for image captures.
- ♦ Paging Terrain Timeout. If the terrain does not finish paging in by the time the timeout value has been reached, take the image.
- ♦ Metadata Time Source. The source of the time stamp to include with an image as metadata. Metadata is published only when sending National Imagery Transmission Format (NITF) images. (For details about choosing the image format, please see “[Configuring Image Properties](#),” on page 3-5.)
- ♦ Flip Images Vertically, Flip Images Horizontally. Flip the image in the indicated direction before it is sent.

RadarFX server settings are saved automatically when the application exits.

### To configure RadarFX Server:

1. Choose **Settings** → **Application**. The Application Settings dialog box opens.
2. Select the RadarFX Server Settings page ([Figure 2-2](#)).

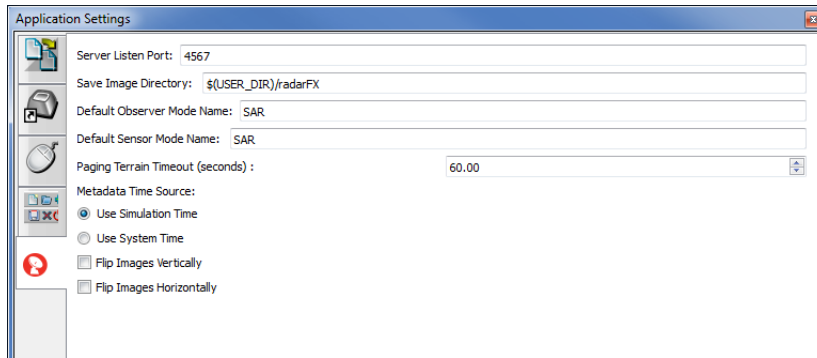


Figure 2-2. RadarFX Settings page

3. Change parameter settings as desired.



## 2.5. Configuring Sensors

For general details about configuring sensors, please see Section 1.5, “[Configuring SensorFX Sensors](#),” in *SensorFX Users Guide*. The parameters for the SAR and MMW sensors are described in [Table 2-1](#).



RadarFX Server uses SensorFX sensors. The discussion of CameraFX sensors in *VR-Vantage Users Guide* does not apply.

Table 2-1: Parameters for SAR and MMW sensors

| Parameter                      | Description                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                 |
|--------------------------------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| AGC                            | Automatic Gain Control. With AGC on, the maximum received power (and thus saturation ratio) will be computed as the power estimated to be returned by a surface of unit less areal RCS = 0.25 at the boresight range, disregarding atmospheric, but including system noise.<br>Default: OFF.                                                                                                                                                                                                                                                |
| Doppler Coloring               | (MMW only) A display parameter that color-codes returns according to their perceived velocity relative to the sensor. The intensity of the return is not altered, but the color shifts to red (away from sensor) or blue (toward sensor) by an amount proportional to the position of the return in the detectable Doppler scale, the maximum velocity of which is governed by the wavelength and pulse repetition frequency (PRF), and the minimum of which is determined by the wavelength and time-on-target.<br>ON or OFF. Default: OFF |
| Toggle Image Orientation       | (SAR only) Rotates the image orientation by 180 degrees.                                                                                                                                                                                                                                                                                                                                                                                                                                                                                    |
| Region of Interest Down-range  | (SAR only) The desired downrange extent of the section of terrain to be mapped, relative to the current boresight terrain intersection point.<br>Nominal values in range 100-1000.                                                                                                                                                                                                                                                                                                                                                          |
| Region of Interest Cross-range | (SAR only) The desired cross range extent, in meters, of the section of terrain to be mapped, relative to the current boresight terrain intersection point.<br>Nominal values in range 100-1000.                                                                                                                                                                                                                                                                                                                                            |

Table 2-1: Parameters for SAR and MMW sensors

| Parameter                      | Description                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                        |
|--------------------------------|--------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Center Frequency               | <p>The carrier frequency of the radar. It affects atmospheric transmission loss and noise, beam width, Doppler resolution, and wavelength. Higher values improve crossrange positional resolution (beam width), and downrange Doppler resolution, at the expense of a smaller effective receiver area. Typical values are:</p> <ul style="list-style-type: none"> <li>♦ L-band: 1-2 GHz</li> <li>♦ S-band: 2-4 GHz</li> <li>♦ C-band: 4-8 GHz</li> <li>♦ X-band: 8-12 GHz</li> <li>♦ Ku-band: 12-18 GHz</li> <li>♦ Ka-band: 30-40 GHz</li> <li>♦ MMW band ~ 40 - 300 GHz</li> <li>♦ W-band: 90-100 GHz.</li> </ul> |
| Pulse Width                    | <p>The width of the radar transmitter's pulses, in microseconds. It is inversely proportional to bandwidth. Lower values improve downrange positional resolution and increase the received signal. Higher values reduce system noise.</p> <p>Should be smaller than <math>1/\text{PRF}</math>. Typically <math>1.E-9</math> to <math>1.E-2</math> [s].</p>                                                                                                                                                                                                                                                         |
| Pulse Repetition Frequency     | <p>The frequency, in Hz, with which the transmitter sends pulses of RF power. Lower values increase the maximum unambiguous range and received signal, but decrease maximum detectable Doppler shift.</p> <p>Should be smaller than <math>1/\text{PW}</math> and <math>c/2\text{DR}</math>, where <math>c</math> is speed of light and <math>\text{DR}</math> is downrange region of interest. Should be greater than about <math>V/L</math>, where <math>V</math> is intended aircraft speed and <math>L</math> is integration path length. Typically 250-300000 Hz.</p>                                          |
| Transmitter Polarization Angle | <p>Linear polarization angle of transmitter gain, in degrees. Typical values:</p> <ul style="list-style-type: none"> <li>♦ Horizontal = 0</li> <li>♦ Vertical = 90.</li> </ul> <p>Default = 45.</p>                                                                                                                                                                                                                                                                                                                                                                                                                |
| Transmitter Directivity        | <p>Similar to a lobe-width parameter, in that larger values focus the transmitter gain pattern into a smaller, but stronger, main lobe centered at the boresight direction. A value of 1 results in no focusing, that is, a Unity gain pattern.</p> <p>Must be greater than zero, but typically set <math>\geq 1</math>.</p>                                                                                                                                                                                                                                                                                       |

Table 2-1: Parameters for SAR and MMW sensors

| Parameter                   | Description                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                  |
|-----------------------------|--------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Receiver Polarization Angle | <p>Linear polarization angle of receiver acceptance pattern, in degrees. Typical values:</p> <ul style="list-style-type: none"> <li>♦ Horizontal = 0</li> <li>♦ Vertical = 90.</li> </ul> <p>Default = 45.</p>                                                                                                                                                                                                                                                                                               |
| Receiver Directivity        | <p>Similar to a lobe-width parameter, in that larger values focus the receiver acceptance pattern into a smaller but stronger main lobe centered at the boresight direction. A value of 1 results in no focusing. Increasing values also increase effective receiver area.</p> <p>Must be greater than zero, but typically set <math>\geq 1</math>.</p>                                                                                                                                                      |
| Integration Path Length     | <p>(SAR only) The distance over which the radar collects returned pulses, also known as the SAR antenna length. Higher values improve cross range resolution.</p> <p>Should be greater than desired cross range region of interest, and greater than <math>c/(2\delta f)</math>, where <math>c</math> is light speed and <math>f</math> is center frequency in Hz. The effect of very high values will be limited by terrain texture resolution, display resolution, or both.</p> <p>Typically 100-10000</p> |
| Emitter Power               | <p>The power emitted by the radar transmitter. Higher values improve effective image gain. Decreasing power results in a darker image.</p> <p>Must be greater than zero. Typically 50-5000.</p>                                                                                                                                                                                                                                                                                                              |
| System Temperature          | <p>Unavoidable internal radar system noise temperature. Higher values degrade signal-to-noise ratio.</p> <p>Must be greater than zero. Typically 270-850 degK.</p>                                                                                                                                                                                                                                                                                                                                           |
| Saturation S/N Ration       | <p>The Signal-to-Noise ratio at which the return pulses saturate the receiver electronics. In other words, this ratio defines the maximum received power of the system, when multiplied by the noise power. Higher values will decrease image intensity.</p> <p>Must be greater than zero, but typically set <math>\geq 1</math>.</p>                                                                                                                                                                        |
| Gain Pattern                | <p>Allows focusing of the emitted or received RF power into lobes. Both the transmitter and receiver share the same gain/acceptance pattern, but can have different directivities. Possible values:</p> <ul style="list-style-type: none"> <li>♦ Unity (no lobes).</li> <li>♦ Lobe (single-lobe).</li> <li>♦ Rect. Rectangular (main lobe plus side lobes).</li> </ul>                                                                                                                                       |

Table 2-1: Parameters for SAR and MMW sensors

| Parameter                 | Description                                                                                                                                                                                                                                                                                                                                                                                                                                              |
|---------------------------|----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Display Type              | <p>Specifies which computed ratio the display is sensitive to.</p> <ul style="list-style-type: none"><li>♦ Scaled Power: Ratio of received power to maximum power.</li><li>♦ Scaled Radiance: Ratio of received radiance to maximum radiance.</li><li>♦ Scaled Effective RCS: Ratio of received power to power estimated to be returned by a surface of unit RCS at the boresight range, disregarding atmospheric, but including system noise.</li></ul> |
| Intensity Modulation Gain | <p>Together with the geometry-model-specific material classification (IMOD) files, this governs the extent to which detail variance present in the RGB texture for the entity or terrain models are translated into additional RCS variance in the radar scene.</p>                                                                                                                                                                                      |



## 3. Using the RadarFX Simple Client

This chapter explains how to use the RadarFX Simple Client.

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| Requesting an Image.....                             | 3-3 |
| Specifying the Sensor.....                           | 3-3 |
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| Creating a Configuration Preset.....                 | 3-6 |
| Loading a Configuration Preset .....                 | 3-6 |

### 3.1. Starting the Simple Client

The typical use of RadarFX is to embed its functionality into a third-party client application. The client application requests an image from the RadarFX, which provides an image based on the location information sent from the client. The RadarFX Simple Client demonstrates what you can do with the RadarFX API.

#### To start the RadarFX Simple Client:

1. If you are using Windows 7, on the Start menu, choose **All Programs** → **MÄK Technologies** → **RadarFX 1.1** → **RadarFX Simple Client**.

If you are using Windows 10, on the Start menu, choose **All apps** → **MÄK Technologies** → **RadarFX Simple Client**.

RadarFX Simple Client opens and the Connect to RadarFX Server dialog box opens.

2. In the Connect to RadarFX Server dialog box, accept the default values. Click OK. The RadarFX Simple Client opens ([Figure 3-1](#)).

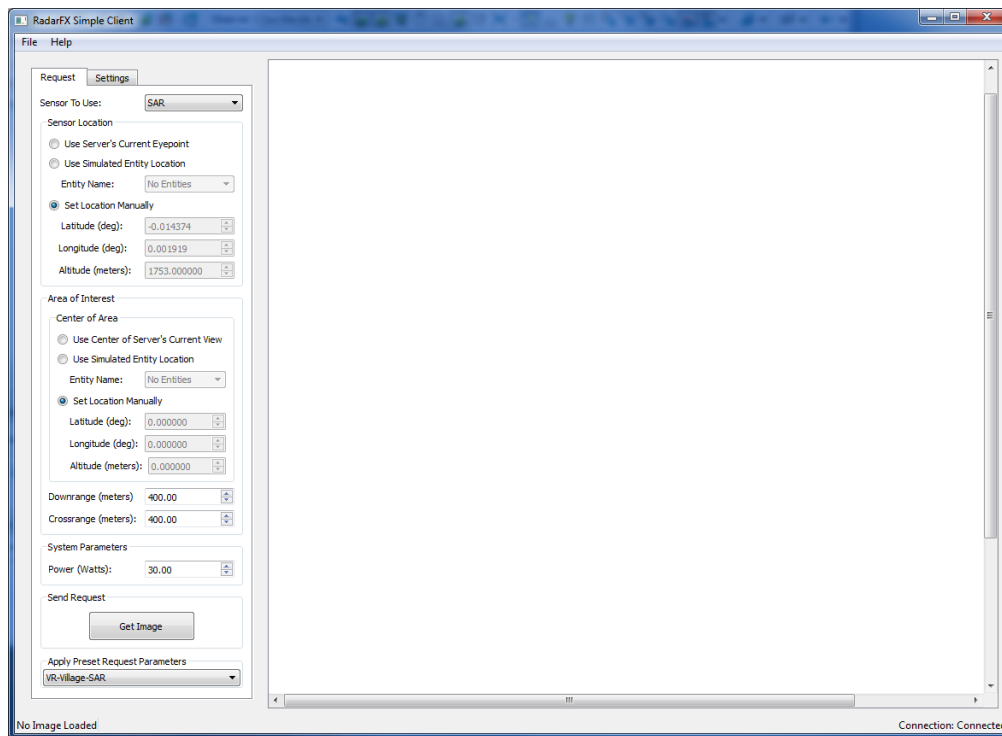


Figure 3-1. RadarFX Simple Client

## 3.2. Requesting an Image

You can create presets for frequently used configuration settings so that you do not have to enter them every time you use the client application. For details, please see [“Creating a Configuration Preset,”](#) on page 3-6.

**To request an image from the server, you:**

1. Specify the sensor to use.
2. Specify the location of the sensor.
3. Specify the area of interest.
4. Set the power to use.
5. Send the request.

### 3.2.1. Specifying the Sensor

The client gets a list of sensors from the server. RadarFX users typically use the SAR sensor.

**To specify the sensor to use:**

1. In the RadarFX Simple Client window, select the Request tab.
2. Select an option in the Sensor to Use list.

### 3.2.2. Specifying the Location of the Sensor

You must tell the server where the sensor that will take the image is located. You can:

- ♦ Use the location of the server’s observer. This option is most useful when both the server and the client are running on the same machine and you can manually move the observer into position and then request a radar image.
- ♦ Attach to an entity in the simulation (if the server is connected). The client gets a list of entities from the server. The client does not need to be connected to the simulation.
- ♦ Enter a location manually in latitude, longitude, and altitude.

**To specify a location:**

1. In the Sensor Location group box, choose one of the options.
2. If you choose Use Simulated Entity Location, select an entity in the Entity Name list.

If you choose Set Location Manually, specify Latitude, Longitude, and Altitude.

### 3.2.3. Specifying the Area of Interest

The area of interest is the area that you want to take an image of. The sensor does not have to be located in the area, although it could be. You can specify the area of interest as:

- ♦ An area centered on the server's eyepoint.
- ♦ An area centered on a simulated entity.
- ♦ An area specified by its latitude, longitude, and altitude.

The cross range and down range values specify the size, in meters, of the area of interest centered on the target location, as illustrated in [Figure 3-2](#).

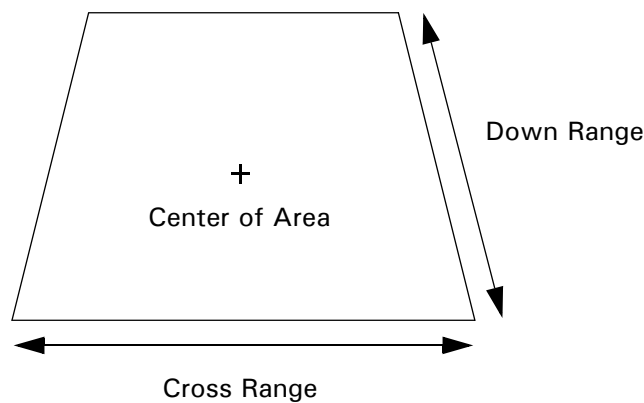


Figure 3-2. Area of interest

**To specify the area of interest:**

1. In the Center of Area group box in the Area of Interest group box, select an option.
2. If you choose Use Simulated Entity Location, select an entity in the Entity Name list.

If you choose Set Location Manually, specify Latitude, Longitude, and Altitude.

3. Specify the down range in the Downrange box.
4. Specify the cross range in the Crossrange box.

### 3.2.4. Specifying the Power

The power value is the amount of power that the SAR system should use to generate the image. Higher power levels increase the image gain. Lower levels result in a darker image.

- To specify the power, in the System Parameters group box, enter a value in the Power box.



### **3.2.5. Requesting the Image**

When you request an image, the client sends the request to the server. The server returns the image and it is displayed in the client window.

- To request the image, in the Send Request group box, click Get Image.

## ***3.3. Configuring Image Properties***

You can specify the properties of the image that the server returns. You can also specify that the image be saved on the server. You can specify the following properties:

- ♦ Image size, in pixels.
- ♦ Image Rotation. The image can be rotated so that North is up or the sensor's view is up.
- ♦ Image Format. Options are PNG, JPG, BMP, Raw, and NITF (National Imagery Transmission Format).
- ♦ Image Data Type. Byte, short, or float.

**To specify image properties:**

1. In the Simple Client window, select the Settings tab.
2. In the Image group box, change properties as desired.
3. To save the image on the server, in the Save Options group box, select Save On Server. Specify the directory in which to save images.

## ***3.4. Saving and Loading Images on the Simple Client***

You can save the images you get from the server. You can load images that you have saved.

- To save an image, choose **File** → **Save Image**, and specify a name and location for the image.
- To load an image, choose **File** → **Load Image**, and select the image to load.

### 3.5. Creating a Configuration Preset

The client includes several preset configurations for the terrains that are shipped with RadarFX Server. The presets are stored in `./userData/radarFX/defaultClientPresets.json`. You cannot save configurations through the graphical user interface (GUI). The following is one of the presets included. To create your own, copy a block of code and change the values as desired.

```
{
  "name": "VR-Village-SAR",
  "ownshipLocation": {"lat": -0.014374, "lon": 0.001919, "alt": 1753},
  "targetLocation": {"lat": 0, "lon": 0, "alt": 0},
  "downrange": 400,
  "crossrange": 400,
  "power": 30,
  "sensor": "SAR (SensorFX)",
  "imageRotation": "North Up",
  "imageX": 1280,
  "imageY": 1024,
  "imageFormat": "PNG"
},
```

#### 3.5.1. Loading a Configuration Preset

- To load a preset, in the Apply Preset Request Parameters group box, select a preset from the list.



## 4. Adding GenesisMC Models to RadarFX

This chapter explains how to integrate materially classified models created with GenesisMC into RadarFX.

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## 4.1. Introduction

GenesisMC is an application created by JRM Technologies that processes models and creates the files needed by RadarFX to render them based on material classification. This chapter assumes you have generated material classified versions of your models using GenesisMC and explains how to set up the files for RadarFX to use them.

## 4.2. Model File Setup

RadarFX uses the following types of files to load the materially classified version of a model:

- Material classification file (*.emat*).
- Material system file (*.ms*).
- Intensity modulation file (*.imod*) (optional).

These files are generated by GenesisMC.

RadarFX uses the names of the textures and models to look for the material classified configuration files. For example, the base set of files for the SH-60 SEA-HAWK (in *.data/Vehicles/RotaryWing/SH-60 SEA-HAWK*) before material classification is:

- DB\_ROTOR\_4PALES\_128\_rgba.meif
- DB\_SH60L\_1024\_DESERT\_CAMO\_NML\_rgb.meif
- DB\_SH60L\_1024\_DESERT\_CAMO\_RFL\_rgb.meif
- DB\_SH60L\_1024\_DESERT\_CAMO\_rgb.meif
- DB\_SH60L\_1024\_DESERT\_CAMO\_SPC\_rgb.meif
- DB\_SH60L\_1024\_rgb.meif
- DB\_SH-60L\_DESERT\_CAMO\_V7.0.medf
- DB\_SH60L\_FLOOR\_256\_rgb.meif
- DB\_SH60L\_INTERIOR\_512\_rgb.meif
- DB\_SH60L\_SHADOW\_256\_rgba.meif
- DB\_SH60L\_WINDOW\_512\_RFL\_rgba.meif
- DB\_SH60L\_WINDOW\_512\_rgba.meif
- DB\_SH60L\_WINDOW\_512\_SPC\_rgba.meif

### 4.2.1. The *.emat* Files

EMAT files are materially classified versions of the visual RGB textures. One of the RGB textures for the SH-60 is DB\_SH60L\_1024\_rgb.meif. After processing the textures, GenesisMC creates three EMAT textures for *DB\_SH60L\_1024\_rgb.meif*—*DB\_SH60L\_1024.emat1.dds*, *DB\_SH60L\_1024.emat2.dds*, and *DB\_SH60L\_1024.emat3.dds*. RadarFX does not use the *emat1* file. In order to save texture memory, RadarFX uses the *.imod* file to fulfill the same purpose.

Copy the \*.emat2.dds and \*.emat3.dds files to the same directory as the RGB textures so that RadarFX can find them. The complete list of .emat files for the SH-60 is as follows:

- DB\_ROTOR\_4PALES\_128.emat2.dds
- DB\_ROTOR\_4PALES\_128.emat3.dds
- DB\_SH60L\_1024.emat2.dds
- DB\_SH60L\_1024.emat3.dds
- DB\_SH60L\_1024\_DESERT\_CAMO.emat2.dds
- DB\_SH60L\_1024\_DESERT\_CAMO.emat3.dds
- DB\_SH60L\_FLOOR\_256.emat2.dds
- DB\_SH60L\_FLOOR\_256.emat3.dds
- DB\_SH60L\_INTERIOR\_512.emat2.dds
- DB\_SH60L\_INTERIOR\_512.emat3.dds
- DB\_SH60L\_WINDOW\_512.emat2.dds
- DB\_SH60L\_WINDOW\_512.emat3.dds.

#### 4.2.2. Material System File (.ms)

RadarFX uses the material system file to map a channel of the emat texture to a particular material. There might be multiple material system files in the GenesisMC output directory. The one that RadarFX needs ends in *Emat.ms*. The contents of the file will be nine lines that define six materials. In the SH-60 example, this file is *DB\_SH-60L\_DESERT\_CAMO\_V7.0Emat.ms*.

There are two ways to point to a material system file. The simplest way is to give the file the same name as the model file name minus the extension and add *Emat.ms*. This file must be in the same directory as the model file. In the SH-60 example, the model file name is *DB\_SH-60L\_DESERT\_CAMO\_V7.0.medf*. Therefore, the material system file is *DB\_SH-60L\_DESERT\_CAMO\_V7.0Emat.ms*.

The other way to point to a material system file is in a model definition. For details, please see “[The msFilename Parameter](#),” on page 4-4.

#### 4.2.3. Intensity Modulation File (.imod)

An intensity modulation file or .imod file is an optional file that defines how much of the RGB texture to mix with the sensor response in the final result. It allows the intensity modulation to be defined on a per-material and per-sensor band level. The file must have the same name as the material system file, except that the extension must be .imod instead of .ms. This file must be in the same directory as the material system file. In the SH-60 example the material system file is *DB\_SH-60L\_DESERT\_CAMO\_V7.0Emat.ms* which corresponds to intensity modulation file *DB\_SH-60L\_DESERT\_CAMO\_V7.0Emat.imod*.

### **4.3. Model Definitions for Materially Classified Models**

If you have generated material classification files for a model that is already configured in VR-Vantage, all you have to do is put the required files in the model directory as described in previous sections. You do not have to edit the model definition.

If you have created a new model, you must create a model definition, as described in Section 28.3, “[Creating and Editing Model Definitions](#),” in *VR-Vantage Users Guide*.

RadarFX supports an optional parameter, **msFilename**, that you can add to schemas and model definitions.

#### **4.3.1. The msFilename Parameter**

The **msFilename** parameter lets you point to a material system file that does not use the naming convention described in “[Material System File \(.ms\)](#),” on page 4-3. Possible reasons for this are if there are two models that need to use the same material system file or there are multiple variations of the same model that need different material systems.

The **msFilename** parameter is not available by default. You must be added to the model’s schema before you can use it. Please see Section 28.2.4, “[Adding a Parameter to a Schema](#),” in *VR-Vantage Users Guide* for information about how to add a parameter to a schema.

The parameter must be called **msFilename** and have its type set to string.

To determine which schema to edit, look at the schema listed for the model definition for the model you are editing. The most likely schemas are Entity and Watercraft.



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