

Vision-RTK 2 Release Notes

Release v2.123.7

MAY, 2026

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1 Overview

This release consists of the following artifact:

Image: fp_release-vr2_2.123.7-576-vrtk2

At the time of release, the following support documents and code are valid:

- Documentation
 - Release notes (this document): VRTK2_v2.123.7_release notes_v1.pdf
 - Integration manual: VRTK2_integration_manual_v2.3.4.pdf
 - Datasheet: VRTK2_Datasheet_v1.1.pdf
- Support software
 - Fixposition-driver-8.1.0 or later https://github.com/fixposition/fixposition_driver/tree/8.1.0
 - Fixposition SDK: <https://github.com/fixposition/fixposition-sdk>

Note: The Fixposition SDK is now a submodule of the SDK. When switching to the new driver tag, updating this submodule from within the driver's directory is required.

For any questions or issues, please contact Fixposition support at support@fixposition.com.

2 Release notes

The changes described here are with respect to the release 2.123.6.

When updating from any other release than 2.123.6 or before, please run a factory reset after updating to 2.123.7. This is to prevent any unexpected behavior. For more information, see 'Known Limitations' below.

Downgrading the software after updating is not recommended. If you need to downgrade, get in contact with us.

2.1. Positioning

- Improved performance and stability in GNSS degraded conditions.
- Improved covariance estimation in certain conditions, namely in correction outage scenarios

2.2. GNSS

2.3. Web interface

- Added UI for configuring PTP DSCP IP packet parameters, see Section 3

2.4. Data interface

- Add feature for configurable PTP DSCP IP packet parameters, see Section 3. Default values are 46 for General and Event.
- Increased update rate of status updates on the FP_A-ODOMSTATUS message.

2.5. Other

- Fix LAM client

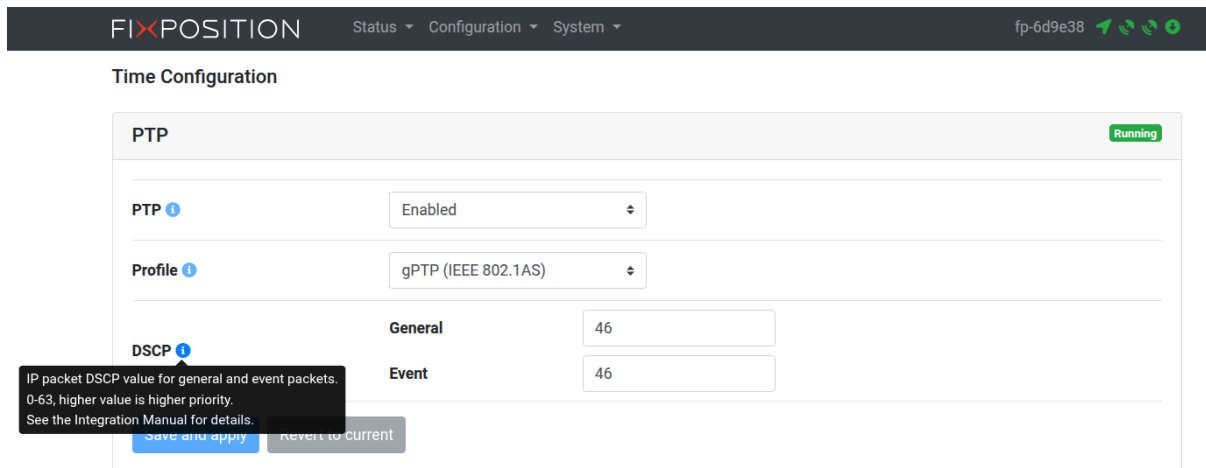
2.6. Known limitations

- Upon updating, the priorly saved biases are deleted and users need to converge the IMU (and if enabled wheel odometry) by moving for around 80-100 meters while receiving RTK Fix signals. **Only then**, it is possible to use the **load position** feature. Please note that this process is only necessary at first time use or after factory resets when no IMU bias data is available.
- **Downgrading:** As a precaution downgrading the firmware is not recommended anymore, and if needed, it requires some instructions from us. Contact support@fixposition.com. Please do not downgrade after updating to 2.123.6. Not following the recommended use and instructions may cause unexpected behavior or damage.
- **Note:** Upgrading to this version from any other version than the [last customer releases](#) (2.85.3, 2.102.2, 2.102.4, 2.102.5, 2.102.6, or 2.102.7), such as other “Beta” versions, may require a factory reset. If you see anything funny, do a factory reset and inform us.
- Users of the beta versions 2.123.3 and 2.123.5 may lose their configuration when updating to 2.123.6. This does not apply to users of the last customer releases 2.102.7 etc. A recommended update procedure for these beta users is: create a config backup (System > Tools), update to 2.123.6, verify the configuration and fix whatever is missing.
- The Save/Load feature is still in an experimental state. Kindly share any bad experiences with us. Generally, it is only possible to use this feature if the last position of the platform is saved and the platform shuts off and is not moved anymore. We only support reliable initialization of Fusion by loading this last position if the platform has not moved from its original last position.
- As described in [our documentation](#), the altitude of the NMEA-GN-GGA refers to the altitude above the respective ellipsoid instead of the orthometric height according to the NMEA standard
- Fusion does not detect bad warmstart parameters (after changing config or platform). Reset data on the ‘System > Tools’ page if config or mount has been changed.
- When recording (to external disk) powering off (by cutting power) or unplugging the USB disk too early may lead to data loss in the recording. Use the web interface or API to download the recordings, unmount the disk or shutdown the sensor in order to prevent the data loss.
- Only one FP_B-MEASUREMENTS can be handled “per epoch”. That means, all wheelspeed measurements at a certain time must be sent in one FP_B-MEASUREMENT message. This also applies to sending wheel measurement measurements via ROS Driver. Each message published on the `/fixposition/speed` topic has to contain the complete information of all enabled sensors.
- Uploading a backup .json file is only supported within the same product line. Example: Do not upload backup/config files from VRTK-2 to VRTK-2 Plus and vice versa.

3 Highlights

3.1 Configurable PTP DSCP IP packet parameters

With this patch, the VRTK-2 now features a configurable PTP DSCP (Differentiated Services Code Point) IP packet parameter function, fully compatible across all supported PTP (Precision Time Protocol) protocols. This allows for precise Quality of Service (QoS) traffic prioritization on your network.



Defaults: Out of the box, and if PTP is enabled, both the Event and General PTP parameters are pre-configured to 46 (Expedited Forwarding / EF).

Setting the DSCP value to 46 ensures that critical timing packets receive maximum priority and minimum delay/jitter across your network infrastructure, guaranteeing highly accurate synchronization