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Technical Manual Inertial Navigation Set
The Inertial+ is a true inertial navigation system (INS) that is aided by the external GNSS. An inertial sensor block with three accelerometers and three angular rate sensors is used to compute all the outputs. A WGS 84 modelled strapdown navigator algorithm compensates for earth curvature, rotation and Coriolis accelerations while measurements

Inertial and GNSS measurement system
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2 Inertial Navigation Inertial navigation is a self-contained navigation technique in which measurements provided by accelerom-eters and gyroscopes are used to track the position and orientation of an object relative to a known starting point, orientation and velocity. Inertial measurement units (IMUs) typically contain three orthogonal

An introduction to inertial navigation
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VN-200 User Manual
An inertial navigation system is a navigation device that uses a computer, motion sensors and rotation sensors to continuously calculate by dead reckoning the position, the orientation, and the velocity of a moving object without the need for external references. Often the inertial sensors are supplemented by a barometric altimeter and occasionally by magnetic sensors and/or speed measuring devices. INSs are used on mobile robots and on vehicles such as ships, aircraft, submarines, guided missil

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Strapdown inertial navigation technology
An inertial navigation system comprises two-distinct parts; the first is the IMU (inertial measurement unit)—sometimes called the IRU (inertial reference unit). Here we’ll explain what terms like ‘IMU frame’ mean.

What is an inertial navigation system? - OxTS
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An inertial navigation system (INS) is a self-contained device consisting of an inertial measurement unit (IMU) and computational unit. The IMU is typically made up of a 3-axis accelerometer, a 3-axiss gyroscope and sometimes a 3-axis magnetometer and measures the system's angular rate and acceleration. The computational unit used to determine the attitude, position, and velocity of the system based on the raw measurements from the IMU given an initial starting position and attitude.