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Fundamentals of High Accuracy Inertial Navigation (Progress in Astronautics and Aeronautics) by A. Chatfield (Author) 4.0 out of 5 stars 2 ratings. ISBN-13: 978-1563472435. ISBN-10: 1563472430.

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Visual and inertial sensors, in combination, are able to provide accurate motion estimates and are well-suited for use in many robot navigation tasks. However, correct data fusion, and

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hence overall performance, depends on careful calibration of the rigid body transform between the sensors.

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Error propagation is dealt with at length and the propagation of inertial instrument errors is given extensive treatment. "Fundamentals of High Accuracy Inertial Navigation" is divided into three parts: inertial navigation, inertial navigation with aids, and accuracy analysis. The first two parts are designed to give the reader an understanding of the fundamentals without requiring knowledge of the statistical analysis techniques involved in determining the effects of errors on accuracy.

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The FOS accuracy enhancement technique initially segments a noisy input time series, denoted $y(n)$ representing one of the six inertial sensor outputs, into smaller analysis windows that can be treated as stationary data. Each segment is modelled using FOS to extract the

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components of the motion dynamics from the noisy measurements.

Fundamentals of Inertial Navigation, Satellite-based Positioning and their Integration is an introduction to the field of Integrated Navigation Systems. It serves as an excellent reference for working engineers as well as textbook for beginners and students new to the area. The book is easy to read and understand with minimum background knowledge. The authors explain the derivations in great detail. The intermediate steps are thoroughly explained so that a beginner can easily follow the material. The book shows a step-by-step implementation of navigation algorithms and provides all the necessary details. It provides detailed illustrations for an easy comprehension. The book also demonstrates real field experiments and in-vehicle road test results with professional discussions and analysis. This work is unique in discussing the different INS/GPS integration schemes in an easy to understand and straightforward way. Those schemes include loosely vs tightly coupled, open loop vs closed loop, and many more.

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This book covers all aspects of inertial navigation systems (INS), including the sensor technology and the estimation of instrument errors, as well as their integration with the Global Positioning System (GPS) for geodetic applications. Complete mathematical derivations are given. Both stabilized and strapdown mechanizations are treated in detail. Derived algorithms to process sensor data and a comprehensive explanation of the error dynamics provide not only an analytical understanding but also a practical implementation of the concepts. A self-contained description of GPS, with emphasis on kinematic applications, is one of the highlights in this book. The text is of interest to geodesists, including surveyors, mappers, and photogrammetrists; to engineers in aviation, navigation, guidance, transportation, and robotics; and to scientists involved in aerogeophysics and remote sensing.

Explore an insightful summary of the major self-contained aiding technologies for pedestrian navigation from established and emerging leaders in the field. *Pedestrian Inertial Navigation with Self-Contained Aiding* delivers a comprehensive and broad treatment of self-contained aiding techniques in pedestrian inertial navigation. The book combines an introduction to the general concept of navigation and major navigation and aiding techniques with more specific discussions of topics central to the field, as well as an exploration of the future of the field: Ultimate Navigation Chip (uNavChip) technology. The most commonly used implementation of pedestrian inertial navigation, strapdown inertial navigation, is discussed at length, as are the mechanization, implementation, error analysis, and adaptivity of zero-velocity update aided inertial navigation algorithms. The book demonstrates the implementation of ultrasonic sensors, ultra-wide band (UWB) sensors, and magnetic sensors.

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Ranging techniques are considered as well, including both foot-to-foot ranging and inter-agent ranging, and learning algorithms, navigation with signals of opportunity, and cooperative localization are discussed. Readers will also benefit from the inclusion of: A thorough introduction to the general concept of navigation as well as major navigation and aiding techniques An exploration of inertial navigation implementation, Inertial Measurement Units, and strapdown inertial navigation A discussion of error analysis in strapdown inertial navigation, as well as the motivation of aiding techniques for pedestrian inertial navigation A treatment of the zero-velocity update (ZUPT) aided inertial navigation algorithm, including its mechanization, implementation, error analysis, and adaptivity Perfect for students and researchers in the field who seek a broad understanding of the subject, Pedestrian Inertial Navigation with Self-Contained Aiding will also earn a place in the libraries of industrial researchers and industrial marketing analysts who need a self-contained summary of the foundational elements of the field.

Algorithms are a fundamental component of robotic systems. Robot algorithms process inputs from sensors that provide noisy and partial data, build geometric and physical models of the world, plan high-and low-level actions at different time horizons, and execute these actions on actuators with limited precision. The design and analysis of robot algorithms raise a unique combination of questions from many elds, including control theory, computational geometry and topology, geometrical and physical modeling, reasoning under uncertainty, probabilistic algorithms, game theory, and theoretical computer science. The Workshop on Algorithmic Foundations of Robotics (WAFR) is a single-track meeting of leading researchers in the eld of

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robot algorithms. Since its inception in 1994, WAFR has been held every other year, and has provided one of the premiere venues for the publication of some of the field's most important and lasting contributions. This book contains the proceedings of the tenth WAFR, held on June 13-15 2012 at the Massachusetts Institute of Technology. The 37 papers included in this book cover a broad range of topics, from fundamental theoretical issues in robot motion planning, control, and perception, to novel applications.

An updated guide to GNSS and INS, and solutions to real-world GPS/INS problems with Kalman filtering. Written by recognized authorities in the field, this second edition of a landmark work provides engineers, computer scientists, and others with a working familiarity with the theory and contemporary applications of Global Navigation Satellite Systems (GNSS), Inertial Navigational Systems (INS), and Kalman filters. Throughout, the focus is on solving real-world problems, with an emphasis on the effective use of state-of-the-art integration techniques for those systems, especially the application of Kalman filtering. To that end, the authors explore the various subtleties, common failures, and inherent limitations of the theory as it applies to real-world situations, and provide numerous detailed application examples and practice problems, including GNSS-aided INS, modeling of gyros and accelerometers, and SBAS and GBAS. Drawing upon their many years of experience with GNSS, INS, and the Kalman filter, the authors present numerous design and implementation techniques not found in other professional references. This Second Edition has been updated to include: GNSS signal integrity with SBAS Mitigation of multipath, including results Ionospheric delay estimation with Kalman filters New MATLAB programs for satellite position determination using almanac and

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ephemeris data and ionospheric delay calculations from single and dual frequency data New algorithms for GEO with L1 /L5 frequencies and clock steering Implementation of mechanization equations in numerically stable algorithms To enhance comprehension of the subjects covered, the authors have included software in MATLAB, demonstrating the working of the GNSS, INS, and filter algorithms. In addition to showing the Kalman filter in action, the software also demonstrates various practical aspects of finite word length arithmetic and the need for alternative algorithms to preserve result accuracy.

Principles of Synthetic Aperture Radar Imaging: A System Simulation Approach demonstrates the use of image simulation for SAR. It covers the various applications of SAR (including feature extraction, target classification, and change detection), provides a complete understanding of SAR principles, and illustrates the complete chain of a SAR operation. The book places special emphasis on a ground-based SAR, but also explains space and air-borne systems. It contains chapters on signal speckle, radar-signal models, sensor-trajectory models, SAR-image focusing, platform-motion compensation, and microwave-scattering from random media. While discussing SAR image focusing and motion compensation, it presents processing algorithms and applications that feature extraction, target classification, and change detection. It also provides samples of simulation on various scenarios, and includes simulation flowcharts and results that are detailed throughout the book. Introducing SAR imaging from a systems point of view, the author: Considers the recent development of MIMO SAR technology Includes selected GPU implementation Provides a numerical analysis of system parameters (including platforms, sensor, and image focusing, and their influence) Explores wave-target

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interactions, signal transmission and reception, image formation, motion compensation Covers all platform motion compensation and error analysis, and their impact on final image radiometric and geometric quality Describes a ground-based SFMCW system Principles of Synthetic Aperture Radar Imaging: A System Simulation Approach is dedicated to the use, study, and development of SAR systems. The book focuses on image formation or focusing, treats platform motion and image focusing, and is suitable for students, radar engineers, and microwave remote sensing researchers.

This book unifies all aspects of flight dynamics for the efficient development of aerospace vehicle simulations. It provides the reader with a complete set of tools to build, program, and execute simulations. Unlike other books, it uses tensors for modeling flight dynamics in a form invariant under coordinate transformations. For implementation, the tensors are converted to matrices, resulting in compact computer code. The reader can pick templates of missiles, aircraft, or hypersonic vehicles to jump-start a particular application. It is the only textbook that combines the theory of modeling with hands-on examples of three-, five-, and six-degree-of-freedom simulations. Included is a link to the CADAC Web Site where you may apply for the free CADAC CD with eight prototype simulations and plotting programs. Amply illustrated with 318 figures and 44 examples, the text can be used for advanced undergraduate and graduate instruction or for self-study. Also included are 77 problems that enhance the ability to model aerospace vehicles and nine projects that hone the skills for developing three-, five-, and six-degree-of-freedom simulations.

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