



Dual Antenna, GPS-Aided Inertial Navigation Systems INS-DU

 **Inertial Labs**
Attitude is Everything

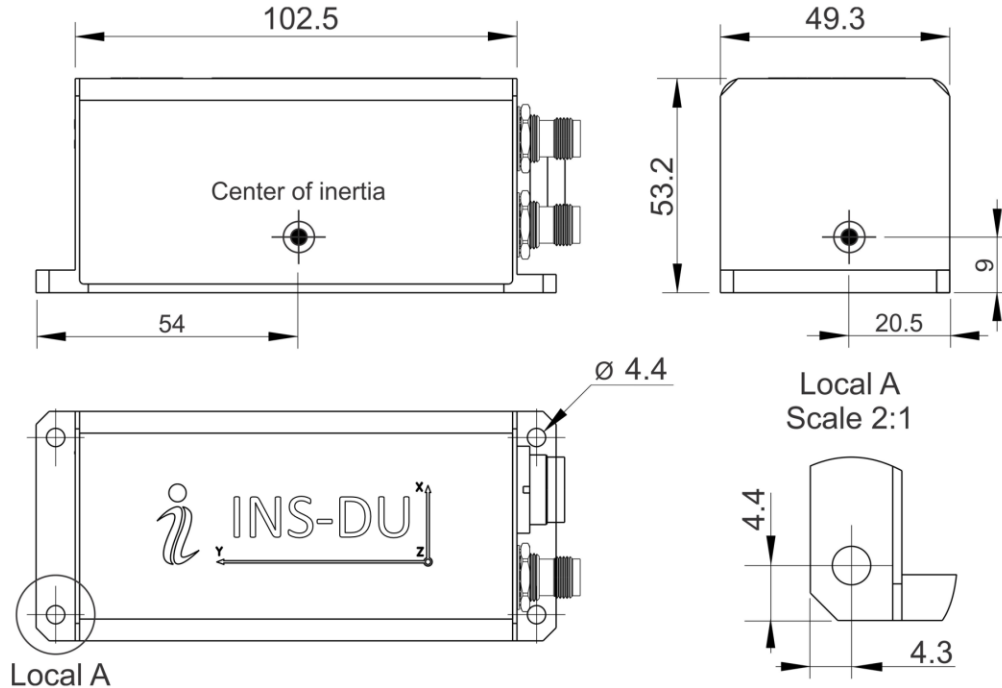


INS-DU Specifications

	Parameter	Units	INS-DU
General	Input signals		<ul style="list-style-type: none"> Marine application: DVL (Doppler Velocity Log) Land application: Odometer, Wheel sensor, Encoder, DMI Aerial application: Wind sensor, Air Speed Sensor, Doppler shift from locator (for long-term GPS denied) All: External Stand Alone Magnetic Compass (SAMC/AHRS)
	Output signals		<ul style="list-style-type: none"> Horizontal and Vertical Positions, Heading, Pitch & Roll, Velocity, Accelerations, Angular rates, Barometric data, PPS Direct AT_ITINS message with Position, Heading, Pitch & Roll to COBHAM AVIATOR UAV 200
	Main features		Low Cost, Dual antenna Heading, 1 cm RTK position
	Data rate (INS)	Hz	Up to 200 (user settable)
	Data rate (IMU)	Hz	Up to 2000 (user settable)
	Start-up time	sec	<1
Navigation	Positions, Velocity and Timestamps		INS-DU
	Horizontal position accuracy (SP, L1), RMS	meters	1.5
	Horizontal position accuracy (SP, L1/L2), RMS	meters	1.2
	Horizontal position accuracy (post processing) ⁽²⁾	meters	0.005
	Horizontal position accuracy (RTK), RMS	meters	0.01 + 1 ppm CEP
	Vertical position accuracy (SP), RMS	meters	<2
	Vertical position accuracy (RTK), RMS	meters	0.02 + 1 ppm CEP
	Velocity accuracy, RMS	meters/sec	0.05
PPS timestamps accuracy	nano sec	20	
Orientation	Heading		INS-DU
	Range	deg	0 to 360
	Static Accuracy ⁽³⁾	deg RMS	0.2 (2m baseline); 0.4 (1m baseline)
	Dynamic accuracy (GNSS) ⁽⁶⁾	deg RMS	0.2 (2m baseline); 0.4 (1m baseline)
	Post processing accuracy ⁽²⁾	deg RMS	0.1
	Pitch and Roll		INS-DU
	Range: Pitch, Roll	deg	±90, ±180
	Angular Resolution	deg	0.01
Static Accuracy in whole Temperature Range	deg	0.1	
Dynamic Accuracy ⁽⁶⁾	deg RMS	0.2	
Post processing accuracy ⁽²⁾	deg RMS	0.05	
GNSS	GNSS receiver		INS-DU
	Number of GNSS Antennas		Dual
	Supported GNSS signals & corrections (optional)		GPS L1C/A L2C, GLO L1OF L2OF, GAL E1B/C E5b, BDS B1I B2I, QZSS L1C/A L2C SBAS L1C/A: WAAS, EGNOS, MSAS, GAGAN
	Channel configuration ⁽⁴⁾		184 Channels – F9 Engine
	GNSS Positions data rate ⁽⁵⁾	Hz	20, 25 ⁽⁶⁾
	RTK corrections		RTCM 3
	GNSS Measurements (raw) data rate	Hz	20
	Velocity accuracy, RMS	meters/sec	0.05
	Initialization time	Sec	<30 (cold start), <1 (hot start)
	Time accuracy (clock drift) ⁽⁷⁾	nano sec	30
IMU	Gyroscopes		INS-DU
	Type		Industrial-grade
	Measurement range	deg/sec	±450, ±950; ±1864
	Bias in-run stability (RMS, Allan Variance)	deg/hr	<2
	Bias residual error over temperature range (RMS)	deg/hr	100
	Angular Random Walk	deg/√hr	0.38
	Accelerometers		INS-DU
	Type		Tactical-grade
	Measurement range	g	±8 g ±15 g ±40 g
	Bias in-run stability (RMS, Allan Variance)	mg	0.005 0.02 0.03
	Bias error over temperature range (RMS)	mg	0.5 0.7 1.2
	Bias one-year repeatability	mg	1.0 1.3 1.5
	Velocity Random Walk	m/s/√hr	0.015 0.035 0.045
	Magnetometers		INS-DU
	Measurement Rate	Gauss	±8.0
Bias in-run stability (Allan Variance)	µGauss	8	
Power Spectral Density	µGauss/√Hz	15	
SF Accuracy	%	0.05	
Electrical and Physical	Environment		INS-DU
	Operating temperature	deg C	-40 to +85
	Storage temperature	deg C	-50 to +90
	MTBF	hours	55,500
	Electrical		INS-DU
	Supply voltage	V DC	9 - 34
	Power consumption	Watts	2.5
	Output Interface (options)		RS-232 or RS-422, CAN Ethernet (optional)
	Output data format		Binary, NMEA 0183 ASCII
	Physical		INS-DU
Size	mm	120 x 50 x 53	
Weight	gram	320	

⁽²⁾ RMS, incremental error growth from steady state accuracy. Post-processing results using third party software; ⁽³⁾ 2 meters base line between two GNSS antennas; ⁽⁴⁾ tracks up to 60 L1/L2 satellites;

⁽⁵⁾ 50 Hz while tracking up to 20 satellites. 20 Hz position update rate for Basic model of INS; ⁽⁶⁾ dynamic accuracy may depend on type of motion; ⁽⁷⁾ time accuracy does not include biases due to RF or antenna delay, ⁽⁸⁾ 20 (GPS+GLO+GAL+BDS or GPS+GLO+GAL) and 25 (GPS only or GPS+GAL/GLO/BDS)



Product Code Structure:

Model	Gyroscope	Accel	Calibration	Connector	Encoder	Color	Datalogger	GNSS receiver	Version	Interface
INS-DU	G450	A8	TMGA	C3	E (option)	B (default)	S64 (default)	ZD9P	VD9	1
	G950	A15				D	S8	WOR		2
	G1864	A40				G				4
						W				5
										11
										22
										145
										245

Example: INS-DU-G450-A15-TMGA-C3-E-B-ZD9P-VD9.1

- INS-DU-OEM: Low Cost Ublox Based GPS-Aided Inertial Navigation System Utilizing MiniAHRS
- G450: Gyroscopes measurement range = ± 450 deg/sec
- G950: Gyroscopes measurement range = ± 950 deg/sec
- G1864: Gyroscopes measurement range = ± 950 deg/sec
- A8: Accelerometers measurement range = ± 8 g \rightarrow recommended for applications with low level of operational vibrations
- A15: Accelerometers measurement range ± 15 g \rightarrow recommended for applications with medium level of operational vibrations
- A40: Accelerometers measurement range ± 40 g \rightarrow recommended for high dynamic applications or/and with high level of vibration
- TMGA: Magnetometers, Gyroscopes and Accelerometers
- C3: 24 pins connector (RS-232, RS-422, CAN, Ethernet interfaces)
- E: Encoder support
- B - Black Color (default)
- D - Desert Color (Desert tan, color code 33446 (tan 686A) per FED-STD-595, Change Notice 1.)
- G - Green
- W - White
- S8: 8GB embedded Data Logger (optional)
- S64: 64GB embedded Data Logger (optional)
- ZD9P: Dual UBlox ZED-F9P GNSS Receivers
- WOR: without GNSS receiver
- VD9: GPS L1/L2, GLO L1/L2, BDS B1/B2, GAL E1/E5, QZSS L1/L5, SBAS, RTK, Dual GNSS Heading, 20 Hz measurements, 20 Hz positions
- VX.1: RS-232 interface
- VX.2: RS-422 interface
- VX.4: CAN interface
- VX.5: Ethernet interface
- VX.11: two RS-232 interfaces
- VX.22: two RS-422 interfaces
- VX.145: RS-232, CAN and Ethernet interfaces (with optional Encoder support)
- VX.245: RS-422, CAN and Ethernet interfaces (without Encoder support)