<table>
<thead>
<tr>
<th>Time</th>
<th>Session</th>
<th>Title</th>
<th>Speaker(s)</th>
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<tbody>
<tr>
<td>08:00</td>
<td>Session</td>
<td>Registration</td>
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<tr>
<td>09:00</td>
<td>Session</td>
<td>Welcome</td>
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<tr>
<td>09:15</td>
<td>Session</td>
<td>In Memory of Kurt Magnus: An Honouring of a Great Scholar of Gyro Technology</td>
<td>P. C. Müller (University of Wuppertal, GERMANY)</td>
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<tr>
<td>09:45</td>
<td>Session</td>
<td>Quartz Vibrating Gyroscopes</td>
<td>(CHAIRMAN: W. Bernard)</td>
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<tr>
<td>10:15</td>
<td>Session</td>
<td>Improved Performance with Quartz Coriolis Vibrating Gyros</td>
<td>J. Guérard, B. Maréchal, O. Le Traon (ONERA, Châtillon, FRANCE)</td>
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<tr>
<td>10:45</td>
<td>Session</td>
<td>Towards North Finding with Quartz Gyroscope Technology</td>
<td>C. Painter, K. Marino (Systron Donner Inertial, Concord, CA, USA)</td>
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<td>11:15</td>
<td>Session</td>
<td>Research on Bell-Shaped Vibratory Angular Rate Gyro’s Character of Resonator with Restraining the Natural Frequency Split</td>
<td>N. Liu, Z. Su, M. Fu, H. Liu, O. Li, Z. Deng, J. Fan, X. Ma</td>
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<td>11:45</td>
<td>Session</td>
<td>HRG and Inertial Navigation</td>
<td>D. Roberfroid, Y. Folope, G. Remillieux (Sagem Défense Sécurité, Paris, FRANCE)</td>
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<td>12:15</td>
<td>Session</td>
<td>Lunch Break</td>
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<td>14:00</td>
<td>Session</td>
<td>MEMS Accelerometers</td>
<td>(CHAIRMAN: W. Schröder)</td>
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<td>14:30</td>
<td>Session</td>
<td>High Performance, Low Cost Inertial MEMS: a Market in Motion</td>
<td>L. Robin, M. Perlmutter (Yole Development, Lyon, FRANCE; Skylight Navigation Technology, Sherborn, MA, USA)</td>
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<tr>
<td>15:00</td>
<td>Session</td>
<td>High Performance Inertial Navigation Grade Sigma-Delta MEMS Accelerometer</td>
<td>P. Zwahlen, Y. Dong, A-M. Nguyen, F. Rudolf, P. Ullah, V. Ragot</td>
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<td>15:30</td>
<td>Session</td>
<td>Inertial Grade Silicon Vibrating Beam Accelerometer</td>
<td>O. Lefort, S. Jaud, R. Quer, A. Mélès (Thales Avionics, Valence, FRANCE)</td>
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<tr>
<td>16:00</td>
<td>Session</td>
<td>Radiation Tolerant Optical Fibers for Fiber Optic Gyroscopes</td>
<td>A. Gillooly, T. Hart (Fibercore Limited, Hampshire, ENGLAND)</td>
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<tr>
<td>16:30</td>
<td>Session</td>
<td>Fiber Optic Gyroscopes for Space Applications, in Orbit Heritage</td>
<td>S. Ferrand, J. Honthaas, G. Cros, A. Faveau, Ph. Guay</td>
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<td>Alternative</td>
<td>Design, Modelling and Fabrication of a Triple-Axis MEMS Gyroscope</td>
<td>Z. Tingkai, W. Wei (Beijing Aerospace Times Optical-Electronic Technology Co. Ltd., Beijing, CHINA)</td>
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Wednesday, September 19, 2012

Session 5: 
FOG and FOG Components 

09:00 One Nautical Mile per Month FOG-Based Strapdown Inertial Navigation System: a Dream Already within Reach? 
Y. Paturel, J. Honthaas, H. Lefevre, F. Napolitano 
(iXBlue, Marly-le-Roi, FRANCE)

09:30 HiBi Single Polariz®HB-Z Zing (TM) Fibers for Fiber Optic Gyroscopes 
J. M. Alvarez, M. Hill, J. Wooler, A. Gillooly 
(Fibercore Limited, Hampshire, ENGLAND)

10:00 Closed Loop Fiber Optical Gyroscopes for Commercial and Space Applications 
Y. Korkishko, V. Fedorov, V. Ponomarev, I. Morev, S. Kostritski, A. Zuev, V. Varnakov 
(RPC OPTOLINK, Moscow, RUSSIA)

10:30 Break

Session 6: 
IMU’s in Dynamic Environment 

11:00 Redundant IMU Borehole Probe for Geological Survey Applications 
M. Perlmuter, A. Pizzarulli 
(Civitanavi Systems Ltd., Zug, SWITZERLAND)

11:30 Application of the Procedure for High-Accuracy IMU Calibration with the Use of a Low-Accuracy Turntable to a Rocking Base 
I. Bogatsky, O. Leonets 
(Kiev, UKRAINE)

12:00 Lunch Break

Session 7: 
Localisation and Surveying 

14:00 Inertial System for Railway Track Diagnostics 
D. Larionov, Y. Filatov, A. Boronachin, L. Podgornaya, E. Bokhman, R. Shalymov 
(St. Petersburg State Electrotechnical University “LETI”, St. Petersburg, RUSSIA)

14:30 Robustness Improvements and Comparisons of Automotive GPS/INS Navigation Filters in Suburban Scenarios Fusing Automotive on-board Sensors 
M. Wankerl, A. Rauch, F. Klanner, G.F. Trommer 
(1)Institute of Systems Optimization, Karlsruhe, GERMANY; 2)BMW Group, München, GERMANY)

15:00 Break

Session 8: 
Pedestrian Navigation 

15:30 Novel Heading Correction Methods for a Foot Mounted Inertial Sensor 
A. C. Hide, B. J. Pinchin, C. T. Moore 
(Nottingham Geospatial Institute, Nottingham, ENGLAND)

16:00 Adaptive Indoor Navigation Using Integration of IMU Based Pedestrian Dead Reckoning and RSS Fingerprinting 
W. Chai, C. Chen, E. Edwan, J. Zhang, O. Loffeld 
(Center for Sensorysystems, University of Siegen (ZESS), Siegen, GERMANY)

16:30 A System for Pedestrian Indoor Localization with Foot Mounted IMU and Additional Sensors 
M. Romanovas, V. Gordko, L. Klingbeil, M. Bourouah, A. Al-Jawad, M. Trächtler, Y. Manoli 
(1)Institute of Microsystems and Information Technology, HSG-IMIT, Villingen-Schwenningen, GERMANY; 2)Institute of Geodesy and Geoinformation, University of Bonn, Bonn, GERMANY; 3)Fritz Huettinger Chair of Microelectronics, IMTEK, Freiburg, GERMANY)

Alternative

An Enhanced Heading Estimation Method in Pedestrian Navigation Systems 
C. Yu, W. Ge, H. Lan, G. Zhou 
(College of Automation, Harbin Engineering University, Harbin, CHINA)

The High Bandwidth’s Measurement and its Influence on the Vibration Characteristic of Fiber-Optic Gyroscopes 
Y.-B. Yang, W. Wang, X. Wang, J. Wang 
(Beijing Aerospace Times Optical-Electronic Technology Co. Ltd., Beijing, CHINA)