

iTraceRT-MVT-510

Accurate Real-Time Multi Vehicle Tracking
with integrated Dynamic Mesh Communication Features
for most accurate automotive Localization & Control Applications

The latest applications in multi vehicle testing require INS/GNSS solutions with high performance, minimum latency and advanced timing features, combined with a robust local and global communication network support, to provide most reliable surveying and trajectory control capability.

iTraceRT-MVT, equipped with iMAR's LINUX^{RT} based real-time signal processing, is the successor of the well-known traditional automotive motion reference system iTraceRT-F4xx/x.

- Fiber Optical Gyro (FOG) based system with gyro-compensating capability ($< 0.5^\circ$ heading determination at static alignment with only single GNSS antenna or even without GNSS access).
- output of angular rate, acceleration, attitude, true heading, course over ground, velocity and position as well as all standard deviations via Ethernet, UART, CAN, USB.
- iDMN Dynamic Mesh Network communication support.
- accuracy: 2 cm position, 0.01° roll/pitch / 0.02° heading under motion, < 0.3 mg acceleration and 0.02 m/s velocity with RTK GNSS.
- latency < 1.2 ms plus jitter < 1 ms for tasks in advanced vehicle control & testing applications.
- all GNSS constellations supported simultaneously, with advanced interference rejection.
- odometer aiding for best performance even during longer GNSS outages.
- 32 GByte internal online data storage with "black-box" capability.
- NTRIP caster capability to be operated as GNSS reference station (i.e. to supply other vehicles with RTK corrections); PTP as option.
- robust, compact, lightweight, advanced EMI/EMC protection.

The iTraceRT-MVT incorporates both, more than iMAR's 25 years of experience in most accurate vehicle trajectory surveying and sensor technology, as well as the latest interface and GUI design rules

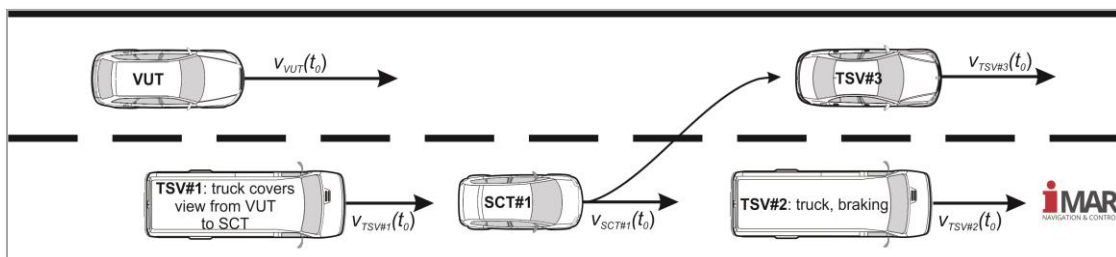
including related data exchange protocols to support both, the traditional highly skilled operators as well as the modern plug & play users.

Besides the iXCOM easy-to-use interface protocol on UART, USB and Ethernet, the powerful GUI allows to be configured according to the skills of the operator, from the professional engineer down to the briefly trained technician or safety driver. A dedicated operation wizard guides the operator step by step through less than a dozen of recommended configuration steps in the vehicle to assure a fast, easy, accurate and straight forward system setup.



The system provides all kinematic measurements and standard deviations of the target vehicle in real-time, with a data update rate of up to 500 Hz with an unbeatable low latency and jitter.

The iTraceRT-MVT series is fully interface compatible to iMAR's iNAT Navigation & Timing system series.



Technical Data: iTraceRT-MVT-510 (rms)

	Rate	Acceleration	Attit./Heading	Position	Velocity	Remarks
Range:	± 600 °/s	± 20 g	unlimited	unlimited	550 ms	> 550 m/s on request
Bias day-to-day:	0.05 °/h	0.3 mg	pure INS, unaided, day-to-day, over temperature range			
Bias instability:	0.01 °/h	0.015 mg	AllanVariance values @ constant temperature			
Bias (filtered):	0.02 °/h	< 0.1 mg	after 5 minutes RTK-GNSS aiding under suffic. dynamics			
Angles:.....			< 0.01° RP, 0.02° Y ¹			(INS/RTK-GNSS)
			< 0.01° RP, 0.02° Y			(after 10 sec RTK-GNSS loss)
			< 0.01° RP, 0.02° Y			(after 60 sec GNSS outage)
			< 0.28° sec lat Yaw			(gyro-compassing, no GNSS)
			0.05° Side slip angle			(v > 10 m/s) ²
Position (horizontal / vertical):				± 2 cm / 5 cm + 2 ppm ¹		(INS/RTK-GNSS) ¹
				± 0.05 m / 0.08 m		(INS, 10 s GNSS outage) ¹
				± 2 m / 0.9 m		(INS, 60 s GNSS outage) ¹
				± 0.3 m / 0.3 m		(INS/ODO, 60 s GNSS outage) ¹
				0.05 % DT (CEP)		(INS/ODO during GNSS outages)
				± 1.8 m		(pure GNSS; CEP50)
				± 2 cm / 5 cm		(post-proc, INS/RTK) ¹
Velocity:					0.01 m/s	(INS/RTK-GNSS) ¹
					0.01 m/s	(10 s GNSS outage.) ¹
					0.02 m/s	(30 s GNSS outage) ¹

Noise:	< 0.0045 °/√h < 40 µg/√Hz	0.003 °	< 1 mm	< 0.005 m/s
Resolution:	< 0.001 °/s < 10 µg	0.000'1 °	< 0.1 mm	< 0.001 m/s
Scale error:	< 0.015 %	< 0.03 %	< 0.02 %	
Linearity error:	< 0.01 %	< 0.02 %	< 0.01 %	

Data fusion (INS/GNSS): tightly coupled INS/GNSS Kalman filter based data fusion (INS/GNSS/ODO)

Data Rate / Latency / Jitter: 500 Hz / < 1.2 ms / < 1 ms

Output (options): UART RS232/RS422 (max. 921.6 kBd), CAN (1 MBd), TCP/IP/UDP (100 MBd), USB Host, iTraceRT-MVT can be operated also as NTRIP caster (like a GNSS reference station); RTK-Base corrections (RS232 or NTRIP); odometer (A or A/B at RS422 level, up to 30 V input)

Inputs: PPS output (RS422 level), PPS timing accuracy better 25 ns; PTP / NTP Time Server (since HW rev. 4); with each PPS a time sync message can be sent via CAN bus.

Synchronization:

Graphical User Interface: MS Windows or LINUX based software [iXCOM-CMD](#) incl. supported features, like integration support wizard (I/F setup, mechanical setup calibration etc.)

Power Supply: 10...34 V DC, approx. 25 W

Temperature, Shock: - 55...+65°C (operating; outer case temperature); 6 g / 20 ms, 6 g rms (10-2'000 Hz) endurance

Mass, Size, Protection: approx. 5.5 kg, approx. 187 x 130 x 261 mm (WxHxD) plus connector; IP67

Environmental Qualif.: MIL-STD-810G, MIL-STD-461G, MIL-STD-704F (full military robustness proven)

Deliverables: iTraceRT-MVT-510, MS Windows based GUI software iXCOM-CMD

Options:

- Dual-antenna configuration for heading aiding at initial standstill (not required, if "stored heading" feature is used together with odometer or initial supervised motion is feasible); 0.2 deg initial accuracy at 1 m dual-antenna baseline
- odometer for aiding during longer GNSS outages (significant advantage for operation in urban canyons)
- **interface to iMAR's iDMN Dynamic Mesh Network** Communication System, capable to serve 100+ vehicles on the proving ground (car-2-base and car-2-car simultaneously with up to video data rate and latency < 50 ms (rms))
- GNSS antenna(s) and GNSS reference station iREF-GNSS
- GSM or GPRS based wireless modem iNetGo for internet based correction data
- compatibility to postproc software InertialExplorer
- [interface to ABD driving robot](#) (via Ethernet)
- fully compatible to the **Proving Ground Installation** [iSWACO-ARGUS](#)

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¹ assumes sufficient GNSS conditions and sufficient motion conditions for filtering state observability; values depend on trajectory
² The side slip angle is the angle between course over ground (CoG) and true heading. It is calculated based on the longitudinal and transversal velocity of the vehicle. It's accuracy therefore increases with increasing velocity. At standstill, the side slip angle cannot be defined.

