iNAT-M200/xLD, iNAT-M200/xLD-DA

MEMS Based Inertial Navigation System with
integrated INS/GNSS/ODO/xxx Data Fusion

iNAT-M200/xLD is a member of the advanced iNAT series (iMAR Navigation and Timing) and one of the smallest powerful MEMS based INS/GNSS inertial navigation, measurement, surveying and control systems on the market for applications on the surface (land/sea) and in the air. It provides all kinematic measurements like acceleration, angular rate, attitude, true heading, velocity and position of the target vehicle in real-time with an data update rate of up to 500 Hz.

- robust, compact, light weight system, 750 grams
- based on high grade MEMS Gyro, Accel technology and up to multi-frequency / multi-constellation GNSS with optional dual-antenna heading and RTK support
- integrated GNSS engine, up to RTK all frequ./const. (4 types of engines available: /TLD, /SLD, /RLD, /MLD)
- Options for high/low range angular rate (-HRR/-LRR) and high range acceleration (-HRA) available
- odometer / wheel sensor aiding capability
- output of angular rate, acceleration, attitude, true heading, CoG, velocity and position in realtime with up to 500 Hz (adjustable)
- several processing modes: Standard mode with 1 m position accuracy and RTK mode with 0.02 m position accuracy
- interfaces: UART RS232 & RS422 / CAN / Ethernet / USB for realtime data output and RS232 for DGPS/RTK correction input; odometer / VMS
- up to 128 GByte internal memory (“black-box”)
- several versions with surveying grade GNSS, economic grade GNSS, standard noise as well as low-noise inertial sensors are available
- easy to use, easy to configure; powerful GUI

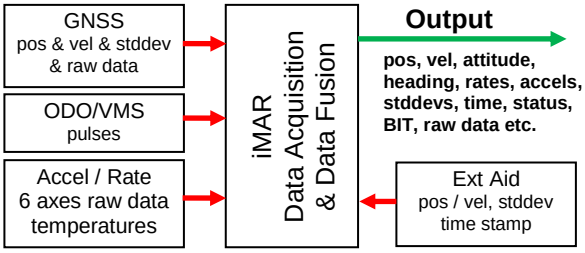
Depending on the application, environmental environment and required realtime accuracy, the data fusion includes INS, GNSS, VMS or any other external sensor providing position and/or velocity, standard deviation and time stamp.

In urban canyons often the number of observable satellites is quite limited and therefore the iNAT-M200/SLD supports an all GNSS constellation data fusion. The 42+ state Kalman filter processing provides a significant better and more robust position and velocity result compared to standard solutions.

For land vehicles additionally an odometer aiding capability is available as an option, the scale factor of the wheel sensor is estimated automatically.

The iNAT-M200/TLD provides system performance and system reliability which is required in standard tasks of navigation, guidance and control, mapping, vehicle motion dynamics testing, trajectory surveying and platform control tasks for cars, trucks, naval vessels, civil and military aircrafts etc.

The **iNAT-M200/MLD** provides the same features, but containing a cheaper commercial grade L1 GPS+GLONASS+GALILEO engine with less robust GNSS solution.



The iNAT-M200 is delivered with the MS Windows (or LINUX or MacOS alternatively) based configuration software iXCOM-CMD. This software allows to configure the output interfaces, furthermore all output data can be displayed and stored online on the user’s notebook, tablet or

process computer. It also allows powerful playback capabilities and provides data export in many formats (csv, xml, GoogleEarth, InertialExplorer, GrafNav). With iREF-GNSS, iMAR also provides a GNSS reference station to provide RTK corrections for centimeter level accuracy on demand.

A powerful postproc software iPosCAL-SURV for batch processing is available to allow post-mission processing including a multi station GNSS correction data solution and a direct visualisation of the results in Google Earth™.

Technical Data iNAT-M200/TLD and iNAT-M200/xLD (typical, rms):

	Rate	Acceleration	Attit./Heading	Position	Velocity	Height
Range[1]:	± 500 °/s	± 8 g	unlimited	unlimited	515 m/s	unlimited
Bias Stability (AV)[1]:	< 2.5 °/h	< 0.1 mg			(without	
Bias (filtered[2]):	< 5 °/h	< 1 mg			export	
Bias day-to-day[3],[1]:	< 0.2 °/s	< 2 mg			control)	
Angles (Attitide, Hdg.):		0.1° / 0.3° | 0.05° / 0.15° RP/Y		(INS / GNSS, w/o | with RTK) [5]		
			0.15° / 0.35° | 0.1° / 0.2° RP/Y	(after 10 s GNSS outage, w/o | with RTK) [5]		
			0.1 deg heading for 2 m baseline in dual-antenna setup (/xLD-DA) [2]			
Position (horizontal plane) [4]:		*for **iNAT-M200/TLD:***	+/- 0.03 m CEP (INS/GNSS RTK real-time) [5]			
				+/- 0.02 m CEP (INS/GNSS RTK post-proc) [5]		
				+/- 0.4 m CEP (INS/GNSS with SBAS)		
				+/- 1.8 m CEP (INS/GNSS)		
				0.8 % of DT CEP (with VMS, during GNSS RTK outage)[6]		
		*for **iNAT-M200/MLD:***	+/- 2 m CEP (INS/GNSS)			
				2 % of DT CEP (with VMS, during GNSS outage)[6]		
Velocity:					0.02 m/s (INS / RTK GNSS)	
Noise:	0.15 °/sqrt(hr)	23 µg/√Hz	0.02 °	< 0.01 m	< 0.01 m/s	
Resolution:	< 0.000'1 °/s	< 20 µg	0.001 °	< 0.001 m	< 0.001 m/s	
Linearity error:	< 0.2 %	< 0.5 %	< 0.2 %			
Scale factor error:	< 0.3 %	< 0.1 %				
Scale factor (filtered)	< 0.1 %	< 0.07 %	< 0.1 %			

INS / GNSS / ODO proc.:	integrated advanced 42+ state INS/GNSS/+ extended Kalman filter data fusion
Internal GNSS Engine:	version /TLN: high performance all frequencies / all constellation RTK GNSS engine (single & dual antenna available) version /SLN: performance up to all frequency / constellation geodedic class RTK GNSS engine (single or dual antenna) version /RLN: commercial multi frequencies / multi constellation RTK GNSS engine (single & dual antenna available) version /MLN: economic grade L1 GPS+GLONASS, SBAS, Beidou, QZSS engine
Data Processing Rate:	up to 500 Hz; PPS timing accuracy better 10 ns
Data Output Rate:	1...500 Hz; all data available in real time, latency < 3 ms, jitter < 1 ms
Synchronisation:	PPS_OUT (RS422 level, latency < 1 µs); 2x EVENT_IN (RS422 or TTL level, latency < 3 ms)
Output (options):	USB, 2 x CAN, 4 x UART RS232/422, Ethernet 100 Mbit/s, NMEA183, ARINC825, TCP/IP, UDP, NTRIP caster with RTCM 104 rev 3 (can serve as a GNSS reference station); NTP Time Server (as of HW rev. 5)
Inputs:	DGPS/RTK correction data from base station, if available (RS232); odometer (A or A/B at RS422 level) as an option
Data Latency:	< 1 ms (sampling accuracy better 1 µs, time-stamped according to PPS; jitter < 1 ms)
Connectors:	MIL-C-38999 III (data), SMA (antenna), M12 (Ethernet)
Integrated Data Storage:	32 GByte (option: 128 GByte); lasts for several days continuous data sampling as "black-box"
Graphical User Interface:	MS Windows or LINUX or MacOS based GUI / HMI software iXCOM-CMD for configuration, visualization, data recording, data converting and playback operation
Power Supply:	9...34 V DC, two independent and isolated inputs available; reverse and overvoltage protection; approx. 8.5 …10 W (dep. on options); < 14 W for < 1 sec after power-on
Temperature; MTBF:	-40...+71 °C (outer case temperature) operating, -40…85 °C storage; 49'000 hrs (AUC, Airborne Uninhabited Cargo, 25 °C)
Shock, Vibration, Altitude:	60 g, 11 ms, 10…2'000 Hz 5 g rms (endurance); 10...2'000 Hz 2 g rms (operational); 60'000 ft
g / g² depenent gyro drift:	< 32 °/h/g / 1.8 °/h/g² (internally compensated)
Mass, size; IP:	approx. 850 grams , ≈102 x 122 x 65 mm (/xLD), 102 x 112 x 65 mm (/MLD); IP67 environm. protection
Operational Support:	Airborne, Ground (with and without odometer), Sea, Subsea; ZUPT (auto or on demand), open interface to feed in application specific aiding information (position, velocity, attitude, heading, standard deviations, time stamp)
Part-Number:	00190-000X4-0Y0Z (X = sensor measurement range, Y = GNSS engine, Z = single/dual-antenna GNSS)
Deliverables:	- MEMS based INS with integrated GNSS receiver, GNSS antenna, cable set - iXCOM-CMD MS Windows or LINUX or MacOS based GUI software
Options:	- L1L2 up to all frequency RTK accuracy of the integrated GNSS receiver - dual-antenna GNSS based true heading (**iNAT-M200/xLD-DA**) allows heading determination even at standstill conditions → typ. 0.2° at 1 m baseline - odometer (VMS) interface for velocity aiding during longer GNSS outages (position error is then correlated to wheel sensor performance, typically 0.1 % longitudinal error of distance travelled) - interface to iMAR's iDMN Dynamic Mesh Network for Swarm Communication & Control - specific algorithms (also customized solutions)

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[1] Option: **iNAT-M200/xLD-LRR/HRR** for low range and high range rate tasks: ±120 °/s (0.15 °/sqrt(hr)), ±2000 °/s (0.3 °/sqrt(hr)) [factory set, can also be combined with –DA option]
Option: **iNAT-M200/xLD-HRA** for high range acceleration tasks: ±40 g °/s (100 µg/sqrt(Hz), 3 mg bias day-to-day) [factory set, can also be combined with –LRR or -HRR]
Option: **iNAT-M200/xLD-HRS** for high range speed tasks: > 515 m/s (requires an export license)
[2] after algorithm converging under sufficient motion excitation with sufficient GPS aiding conditions
[3] values without sufficient INS/GNSS data fusion conditions; the bias are estimated / compensated during GNSS aiding under motion automatically (Kalman filter); iNAT-M200/SLD provides 20 deg/hr bias stability for several hours duration at const. temperature
[4] GNSS based altitude deviation is abut 1.5 times of GNSS based horizontal error; in opposite to iNAT-M200/SxD, the iNAT-M200/MLD does not support RTK; position error of iNAT-M200/**M**LD: < 2 m (CEP)
[5] dependent on trajectory and satellite constellation; in challenging environments (e.g. urban canyons) use iNAT-M200/SLD (RTK not available for iNAT-M200/MLD)
Hint: Under best GNSS and motion conditions the accuracy is 2 cm CEP with RTK.
[6] position error in relation to distance travelled (DT) during GNSS outages (requires a vehicle motion sensor / wheel sensor) – after suffic. GNSS