

## INERTIAL MEASUREMENT UNIT / ATTITUDE HEADING REFERENCE SYSTEM

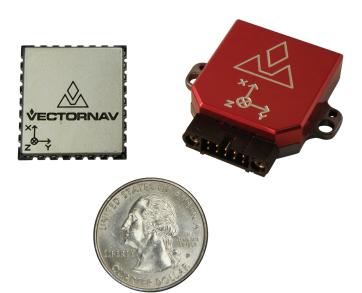
# VN-100 IMU/AHRS

### High-Performance Embedded Navigation

#### PRODUCT OVERVIEW

The VN-100 is a miniature, light weight, low power, high-performance Inertial Measurement Unit (IMU) and Attitude and Heading Reference System (AHRS) available in a surface mount package or aluminum encased Rugged module. Incorporating the latest in MEMS technology, the VN-100 combines 3-axis accelerometers, gyros, magnetometers, a barometric pressure sensor and a 32-bit microprocessor into an extremely compact design.

The VN-100 computes and outputs a real-time, drift-free attitude solution (i.e. 3D orientation) that is continuous over a complete range of 360° motion. All VN-100 sensors go through a rigorous calibration process at the VectorNav production facility to ensure the highest quality inertial measurements and attitude estimates. The small size, high performance, and cost-effectiveness of the VN-100 provides unprecedented opportunities for embedded navigation.



#### **HIGHLIGHTS**

- On-board Extended Kalman filter running at 400 Hz, IMU Data available at 1 kHz
- ➤ Continuous attitude solution over the complete 360° range of motion
- > Static accuracy better than 0.5° in pitch/roll, 2° in heading
- Individually calibrated for bias, scale factor, misalignment,
   & gyro g-sensitivity
- ➤ Available with standard (at +25°C) or full temperature compensation (-40°C to +85°C)
- Surface mount package (30-pin LGA)
   Dimensions: 24 x 22 x 3 mm; Weight: 3.5 grams
- ➤ Rugged package (10-pin Harwin connector)

  Dimensions: 36 x 33 x 9 mm; Weight: 15 grams

#### **FEATURES**

- Vector Processing Engine (VPE) 1.0 Toolboxes
   Real-time magnetic & acceleration disturbance rejection
   Adaptive signal filtering
   Dynamic filter tuning
  - On-board Hard & Soft Iron compensation
- Coning & sculling integrals (ΔV's, ΔΘ's)
- User configurable messages using simple VectorNav binary protocol
- > On-board World Magnetic and Gravity Reference Models
- ➤ On-board gyro drift compensation
- > Multi-sensor synchronization
- ➤ Inputs for external magnetometers or velocity measurements (Airspeed, GPS)
- > Barometric pressure sensor

#### TECHNICAL SPECIFICATIONS

#### **Attitude & Heading**

Range (Heading/Roll): ±180° Range (Pitch): ±90° Static Accuracy (Heading, Magnetic)1: 2.0 ° RMS Static Accuracy (Pitch/Roll): 0.5 ° RMS Dynamic Accuracy (Heading, Magnetic)<sup>1</sup>: 2.0 ° RMS 1.0 ° RMS Dynamic Accuracy (Pitch/Roll)<sup>2</sup>: < 0.05 ° **Angular Resolution:** Repeatability: < 0.2° Output Rate (IMU Data)3: 1 kHz **Output Rate (Attitude Data):** 400 Hz

#### Gyro

Range:  $\pm 2000\,^{\circ}/s$  In-Run Bias Stability:  $< 10\,^{\circ}/hr$  Linearity:  $< 0.1\,^{\circ}/FS$  Noise Density:  $0.0035\,^{\circ}/s\,/Hz$  Bandwidth:  $256\,Hz$  Alignment Error:  $\pm 0.05\,^{\circ}$ 

#### **Accelerometer**

 $\begin{array}{lll} \mbox{Range:} & \pm 16 \ \mbox{g} \\ \mbox{In-Run Bias Stability:} & < 0.04 \ \mbox{mg} \\ \mbox{Linearity:} & < 0.5 \ \mbox{\% FS} \\ \mbox{Noise Density:} & 0.14 \ \mbox{mg}/\sqrt{\mbox{Hz}} \\ \mbox{Bandwidth:} & 260 \ \mbox{Hz} \\ \mbox{Alignment Error:} & \pm 0.05 \ \mbox{°} \end{array}$ 

#### Magnetometer

Range:  $\pm 2.5$  Gauss Linearity: < 0.1 % Noise Density:  $140 \, \mu \text{Gauss} / \sqrt{\text{Hz}}$  Bandwidth:  $200 \, \text{Hz}$  Alignment Error:  $\pm 0.05 \, ^{\circ}$ 

#### **Pressure Sensor**

 Range:
 10 to 1200 mbar

 Resolution:
 0.042 mbar

 Accuracy:
 ±1.5 mbar

 Error Band:
 ±2.5 mbar

 Bandwidth:
 200 Hz

#### **Environment**

min and a second

Operating Temp:  $-40^{\circ}\text{C to } +85^{\circ}\text{C}$ Storage Temp:  $-40^{\circ}\text{C to } +85^{\circ}\text{C}$ 

Electrical:	SIVID	Ruggea
Input Voltage:	3.2 V to 5.5 V	4.5 V to 5.5 V
Current Draw:	45 mA @ 3.3V	40 mA @ 5 V
Max Power		
Consumption:	185 mW	220 mW
Digital Interface:	Serial TTL, SPI	Serial TTL, RS-232

Physical:	SMD	Rugged
Size:	24 x 22 x 3 mm	36 x 33 x 9 mm
Weight:	3.5 g	15 g
Interface:	30-pin LGA	10-pin Harwin

- With proper magnetic declination, suitable magnetic environment and valid hard/soft iron calibration.
- <sup>2</sup> Typical, Velocity Aiding required for applications with sustained linear accelerations.
- <sup>3</sup> Default 800 Hz.

#### **DEVELOPMENT KITS**





VN-100 Development Board

- Pre-Soldered VN-100 Surface Mount Part with USB & RS-232 Interfaces
- 30-Pin Header
- Software Development Kit

VN-100 Rugged Development Kit

- USB & Serial Adapter Cables
- Cable Connection Tool
- Carrying Case
- Software Development Kit

#### **APPLICATIONS**

- > UAVs, UAS, Manned Aircraft
- ➤ Heavy Machinery Monitoring
- Robotics
- ➤ ROVs
- > Smart Weapons
- ➤ Body Motion Capture
- > Head Mounted Displays







#### **DEVELOPMENT TOOLS**

- Sensor Explorer GUI: Powerful and user-friendly GUI allows you to display sensor output as a 3D object, graph inertial data, configure sensor settings, perform data-logging, & more.
- ➤ Software Development Kit: Interface via C/C++, .NET & MATLAB development environments.
- ➤ Online Library: A large collection of inertial navigation knowledge and application notes is available on our website to help maximize VN-100 performance for your application.
- ➤ Engineering Support: Dedicated and responsive engineering support team with combined experience in sensing, guidance, navigation, and controls.
- ➤ Custom Solutions Available: Application-specific modeling & algorithm development; controls & closed-loop navigation solutions; custom form-factors & packaging; integration with other external sensors; displays, GUIs & other software packages; tailored calibrations; custom communication protocols.

© 2016 VectorNav Technologies, LLC. All rights reserved. Specifications subject to change without notice. Version 12-0002-R3