G_{nav} Galaxy Navigation Corp.

AHRS-200[®]

AHRS-200[®] is a high precision strip-down AHRS system which combines ultra-low noise crystal 3-axis gyroscopes, MEMS 3-axis accelerometer, 3-axis magnetometer, barometer and high speed MCU in a single, compact board. All sensors are calibrated over their temperature $\$ bias $\$ scale factor $\$ axis alignment and g-sensitivity in order to make them ideal for the best applications.

While moving and when encountering magnetic distortion, **AHRS-200**[®] employs a patented Kalman filtering algorithm that intelligently fuses with gyros and accelerometers to overcome errors due to erratic motion and changes in the local magnetic field to generate optimal Attitude and Heading data outputs.

Application :

- Stabilization platform control
- Aviation control system (UAV, Fixed wing, Rotor, etc)
- Ground vehicle control
- Underwater vehicle control
- Autonomous vehicle
- Robots

Feature :

- Suitable for primary attitude reference
- All solid state components (no moving parts)
- All sensors have temperature \smallsetminus bias \searrow scale factor \searrow axis alignment calibration
- Auto self-calibrate attitude when system fixed and power on
- Enable 1° to 2° compass heading accuracy
- Dynamic heading accuracy 1.0° (RMS)
- Overcome errors due to erratic motion and changes in the local magnetic field
- 24-bit ADC digital pressure sensor
- Environmentally sealed (waterproof)
- Small size, light weight, compact design
- Low power consumption
- High CP value













Specification

| Gyroscope | | | Attitude | | |
|--|-------------|--------------------------|---|----------|------------------|
| Angular rate (3-axis) | | ±300°/s | Range (Pitch/Roll) | | ±90°/ ±180° |
| Noise density | 0.0 | 004°/s/√ [−] Hz | Static accuracy | | 0.3° |
| Non linearity(Full Scale) |) | ±0.5% | Dynamic accuracy | | 0.5° |
| Accelerometer | | | Resolution | | 0.05° |
| Acceleration (3-axis) | | ±3 g | Update rate | | |
| Noise density | 1 | L20 µg/√Hz | AHRS | | 10 Hz (default) |
| Non linearity(Full Scale) |) | ±0.5% | Power | | |
| Magnetometer | | | Prime power | | 5±5% VDC |
| Magnetic field range (3 | -axis) | ± 8 Gauss | Power consumption | | < 0.5 W |
| Linearity | ± 0.1% | of full scale | Interface and Conn | ector | |
| Field resolution | | 2 mGauss | Interface | | UART, RS-232 |
| Barometer | | | Data connector | | O-type 4-pin |
| Pressure range 300~1,200mbar (9,500m~ -500m) | | | Baud rate 4,800~115,200 bps (default 115,200 bps) | | |
| Resolution | Pressure | 0.02 mbar | Environment | | |
| - | Temperature | 0.01°C | Compensated tempe | rature | – 10°C to +70°C |
| Relative accuracy(700~ | 1000 mbar) | ±0.1 mbar | Operating temperatu | ire | – 40°C to +85°C |
| Long term stability | ± | 1 mbar/year | Vibration | 4 g, l | RMS (20~2000 Hz) |
| Heading | | | Shock | 40 g, 11 | ms 1/2 sine wave |
| Range | | 0~360° | Environmentally seal | ed | IP67 |
| Static accuracy | | 0.5° | Physical | | |
| Dynamic accuracy (RMS | 5) | 1.0° | Dimensions | | 50 x 50 x 22 mm |
| Resolution | | 0.05° | Weight | | <40 grams |
| Magnetic heading | | 1.0°~2.0° | Enclosure | | Aluminum alloy |



1. Power in

- 2. Rx
- 3. Tx
- 4. Ground