Research of AGV Positioning and Navigation System Based on UWB

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- A navigation method combining UWB and inertial measurement unit (IMU) is proposed.
- The time-based wireless positioning principle is used to obtain the UWB positioning data.
- The Kalman filter algorithm is used to fuse the UWB measurement data and IMU calculation data.
- The experimental results show that the error of UWB is less than 75mm in the static condition.