

GNSS

 $R_i, p_i$ 

GNSS

 $R_j, p_j$ 

Prior

 $v_i$ 

IMU

 $v_j$ 

Odom

 $b_{g,i}$ 

Bias

 $b_{g,j}$ 

Bias

 $b_{a,j}$  $b_{a,i}$ 