



Overview

The **IMX-5™** is a 10-DOF sensor module consisting of a triple redundant Inertial Measurement Unit (IMU), magnetometer, and barometer. Data output includes angular rate and linear acceleration. IMU calibration consists of bias, scale factor, cross-axis alignment, g-sensitivity, and temperature compensation.

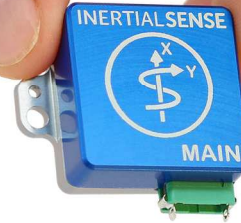
The IMX-5 includes Attitude Heading Reference System (**AHRS**) sensor fusion to estimate roll, pitch, and heading. Adding GNSS input to the IMX-5 enables the onboard Inertial Navigation System (**INS**) sensor fusion to estimate roll, pitch, heading, velocity, and position.

The **RUG-IMX-5-RTK™** combines a multi-frequency GNSS receiver with the IMX-5 enabling the INS sensor fusion to estimate roll, pitch, heading, velocity, and position.

The **RUG-IMX-5-Dual™** combines two multi-frequency GNSS receivers and the IMX-5 onboard INS sensor fusion. Dual GNSS heading can be determined in environments that are challenging for a magnetometer.

Applications

- Drone Navigation
- Unmanned Vehicle Payloads
- Ground and Aerial Survey
- Automotive Navigation
- Stabilized Platforms
- Antenna and Camera Pointing
- First Responder and Trackers
- Health, Fitness, and Sport Monitors
- Robotics and Ground Vehicles
- Maritime



RUG-IMX-5
Size: 25.4 x 25.4 x 11.2 mm
Weight: 10.5 g



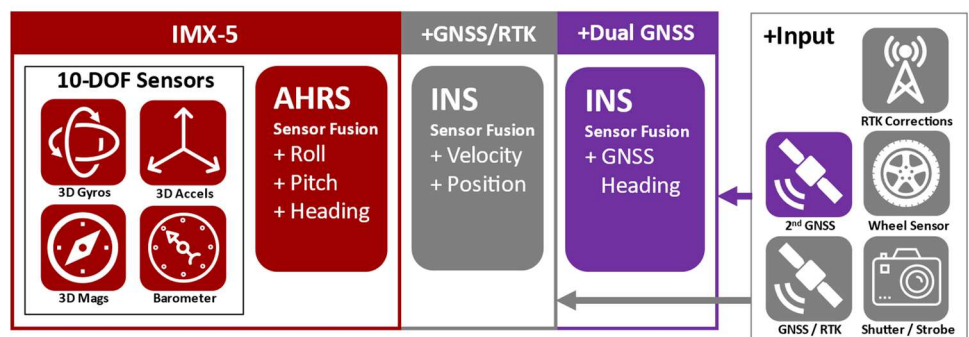
IMX-5
Size: 15.6 x 12.5 x 2.9 mm
Weight: 0.8 g
INS: External GNSS Input



RUG-IMX-5-RTK/Dual
Size: 25.4 x 25.4 x 20.0 mm
Weight: 14 g
GNSS: Multi-Band L1/L2/E5

Features

- **Tactical Grade IMU**
- **Gyro: 2.0 °/hr Bias Instability, 0.2 °/vhr ARW**
- **Accel: 20 µg Bias Instability, 0.04 m/s/vhr VRW**
- **0.03° Roll/Pitch, 0.1° Dynamic Heading**
- **Surface Mount Reflowable (PCB Module)**
- Up to 1KHz IMU and INS Output Data Rate
- External GNSS Support (Multi-Band)
- Attitude (Roll, Pitch, Yaw, Quaternions), Velocity, and Position UTC Time Synchronized
- Triple Redundant IMUs Calibrated for Bias, Scale Factor, Cross-axis Alignment, and G-sensitivity
- -40°C to 85°C Sensor Temperature Calibration
- Binary and NMEA ASCII Protocol
- Barometric Pressure and Humidity
- Strobe In/Out Data Sync (Camera Shutter Event)
- Fast Integration with SDK and Example Software
- Data Logging (SDK and Application Software)





Specifications

Performance (AHRS, INS, RUG)		Typ			
Dynamic Roll/Pitch** (RMS)		0.03°			
Static Heading w/magnetometer (RMS)		2.0°			
Static Heading w/Dual Compass* (RMS)		0.4°			
INS Dynamic Heading** (RMS)		0.1°			
*1 m baseline distance between GNSS antennas.					
**With GNSS input and periodic motion >0.8 m/s² acceleration and >2 m/s velocity.					
Performance (INS, RUG)		RUG	+RTK		
Horizontal Position (w/ SBAS)		1.5 m CEP	1 cm + 1 PPM CEP		
Velocity (GPS and INS)		0.05 m/s			
Angular Resolution		0.05°			
Operation Limits					
Velocity (external GNSS)		500 m/s			
Altitude (external GNSS)		50 Km			
Altitude (Barometric)		10 Km			
Performance		Typ			
Startup Time		0.8 sec			
INS/AHRS Timestamp Accuracy (RMS)		1 us			
Max Output Data Rate (IMU and INS)		1 KHz			
IMU signal latency		4 ms			
Absolute Maximum Ratings		MAX			
Acceleration		10,000 g			
Storage Temperature		-45 to 85 °C	Barometer limitation		
Overpressure		600 kPa			
ESD rating		± 2 kV	Human body model		
Solder Reflow Temperature Max		245 °C			
Solder Reflow Temperature Limit		217 °C liquidus: 40 – 60 s			
Sensors		IMU - Gyros	IMU - Accels	Mags	Pressure
Operating Range		±4000 °/sec	±16 g	±2500 µT	30–125 kPa
In-Run Bias Stability		< 2.0 °/hr	< 20 µg		
Random Walk		0.2 °/vhr	0.04 m/s/vhr		
Non-linearity		0.02 % FSR	0.02 % FSR		
Noise Density		5 mdps/√Hz	60 µg/√Hz		Pa/√Hz
Bias Error over -40C to 85C		0.3 °/s RMS	3,7 mg RMS		
Max Output Rate		1 KHz	1 KHz	100 Hz	50 Hz
Bandwidth		250 Hz	218 Hz	50 Hz	5 Hz
Alignment Error		0.03°	0.03°	0.05°	
Resonant Freq.		2.6/2.17 KHz	20 KHz		
Sampling Rate		8 KHz	4 KHz	300 Hz	200 Hz
Resolution		*0.0076 °/sec	*122 µg	0.3 µT	0.03 Pa
*1KHz resolution after oversampling					(2 cm)
Function		µIMU™	+RTK	+Dual	
Gyro & Accelerometer (IMU)		•	•	•	
Magnetometer & Barometer		•	•	•	
Roll, Pitch, Heading (AHRS)		•	•	•	
Heading, Velocity, Position (INS)			•	•	
GNSS Heading				•	

Electrical (IMX-5)				
Power Draw	Min	Typ	Max	Units
µIMU @ 1KHz		95	105	mW
w/ AHRS, INS @ 250Hz		100	110	mW
Supply Voltage (Vcc)	3.0	3.3	3.6	V
I/O Pin MAX Voltage Range	-0.5		3.6	V
Total Output Current, All Pins			120	mA
I/O Pin Input low-level	0.99			V
I/O Pin Input high-level	2.31	3.3	3.6	V
I/O Pin Output high-level		3.3		V
STROBE input frequency			1	KHz
Rising Slope of VIN*	2.4			V/ms

*The supply rising slope must be higher than minimum rating for proper function.

Electrical (RUG)				
	Min	Typ	Max	Units
Supply Voltage (VIN)	4.0		20	V
RUG-INS-RTK + Antenna				
Current Draw @ 5V, 250Hz*		185		mA
Power Consumption @250Hz*		927		mW
Power Consumption @100Hz*				mW
Power Consumption – Dual		1470		mW

*Navigation filter update rate.

Mechanical (IMX-5)		
		Units
Size	15.6 x 12.5 x 2.9	mm
Weight	0.8	grams

Mechanical (RUG)		
	Units	Conditions
Size	25.4 x 25.4 x 20.0 35.9 x 25.4 x 20.0	W/o mounting tabs W/ mounting tabs
IP Rating	40	No liquid protection
Mounting Tab	30.836	mm
Hole Spacing		
Weight	14.0	grams
Connectors	Main: Harwin# G125-MV11205L1P, GPS 1/2: MMCX	

Communications & I/O		
Interface	UART x3, SPI	
RUG Interface (IS-RUG)	USB, UART x3, RS232, RS485, CAN, SPI	
Max Baud Rate:		
SPI	10 Mbps	
UART, RS422, RS485	3 Mbps	
RS232	500 Kbps	
Strobe Inputs / Outputs	4 / 1	



Development Kits available on our website.

