Block Parameters: AHRS

AHRS

Attitude and Heading Reference System.

The block outputs orientation and bias-corrected angular velocity from IMU measurements. Tune the measurement noises to match a specific sensor. Tune the environmental noises to match the motion characteristics.

| Main | Measurement Noise | Environmental Noise |

Reference frame:	NED
Decimation factor:	1
Initial process noise:	ahrsfilter.defaultProcessNoise *<12x12 double>*
Orientation format:	quaternion
Simulate using:	Code generation

OK   Cancel   Help   Apply