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

Accelerometer noise $((m/s^2)^2)$:   0.0001924722

Gyroscope noise $((rad/s)^2)$:   9.1385e-5

Magnetometer noise $((\mu T)^2)$:   0.1

Gyroscope drift noise $((rad/s)^2)$:   3.0462e-13

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