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Visual and inertial sensors, in combination, are able to provide accurate motion estimates and are well-suited for use in many robot navigation tasks. However, correct data fusion, and hence overall performance, depends on careful calibration of the rigid body transform between the sensors.

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Error propagation is dealt with at length and the propagation of inertial instrument errors is given extensive treatment. "Fundamentals of High Accuracy Inertial Navigation" is divided into three parts: inertial navigation, inertial navigation with aids, and accuracy analysis. The first two parts are designed to give the reader an understanding of the fundamentals without requiring knowledge of the statistical analysis techniques involved in determining the effects of errors on accuracy.

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The FOS accuracy enhancement technique initially segments a noisy input time series, denoted  $y(n)$  representing one of the six inertial sensor outputs, into smaller analysis windows that can be treated as stationary data. Each segment is modelled using FOS to extract the components of the motion dynamics from the noisy measurements.

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