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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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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.