## MTi-680

- Small, IP52-rated RTK GNSS/INS
- 0.2 deg roll/pitch & cm-level position accuracy
- Connects to external RTK GNSS receiver

The MTi-680 is a RTK GNSS/INS with a small form-factor design for deep integration into your application. Building on the proven MTi 600-series technology it enables a robust and easy to use cm-level positioning and orientation tracking. If features a interface to an external RTK GNSS receiver so you can efficiently design your application. It is designed for easy integration and seamless interfacing with other equipment.

The MTi-680 is supported by the MT Software Suite which includes MT Manager (GUI for Windows/Linux), SDK, example codes and drivers for many platforms including ROS.



- White label and OEM integration options available
- 3D models available on request

• Available online via Digi-Key, Mouser, Farnell and local distributors

Sensor Fusion Performance		Mechanical	
Roll, Pitch	0,2 deg RMS	IP-rating	IP51
Yaw/Heading	0.5 deg RMS	Operating Temperature	-40 to 85 °C
Position	<1 cm CEP	Casing material	PC-ABS
Velocity	0.05m/s RMS	Mounting orientation	No restriction, full 360° in all axes
Gyroscope		Dimensions	28x31.5x13 mm
Standard full range	2000 deg/s	Connector	Main: Phoenix Contact 16 pin, 1.27 mm
In-run bias stability	4 deg/h		pitch
Bandwidth (-3dB)	500 Hz	Weight	8.9 g
Noise Density	0.004 º/s/√Hz	Certifications	CE, FCC, RoHS
g-sensitivity (calibr.)	0.001 °/s/g	Electrical	
Accelerometer		Input voltage	4.5 to 24V
Standard full range	10 g	Power consumption (typ)	<1 W
In-run bias stability	10 (x,y) 15(z) μg	Interfaces / IO	
Bandwidth (-3dB)	500 Hz	Interfaces	UART, CAN, RS232
Noise Density	60 µg/√Hz	Sync Options	SyncIn, SyncOut, ClockSync
Magnetometer		Protocols	Xbus, ASCII (NMEA) or CAN
Standard full range	+/- 8 G	Clock drift	— 1ppm (external)
Total RMS noise	1 mG	Output Frequency	Up to 2 kHz, 400 Hz SDI
Non-linearity	0.2%	Built-in-self test	— Gyr, Acc, Mag, Baro, GNSS
Resolution	0.25 mG		e,,,,,ee,,
	0.23 110	Software Suite	
GNSS Receiver		GUI (Windows/Linux)	MT Manager Firmware updater,
Brand	External		Magnetic Field Mapper
Model	External	SDK (Example code)	C++, C#, Python, Matlab, Nucleo,
RTCM input port	External		public source code
Barometer		Drivers	LabVIEW, ROS, GO
Standard full range	300-1250 hPa	Support	BASE by XSENS: online manuals,
Total RMS noise	1.2 Pa		community and knowledge base
Relative accuracy	+/- 8 Pa (~0.5m)		



