MTi-610

- Small, IP51-rated IMU
- Factory-calibrated inertial data

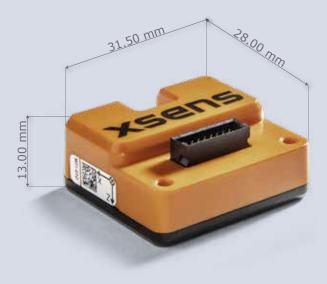
• Full Graphical User Interface (GUI) and Software Development Kit (SDK) available

The MTi-610 is a Inertial Measurement Unit 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 motion tracking. It is designed for easy integration and seamless interfacing with other equipment.

The MTi-610 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.

IMU performance

IMU performance	
Accelerometer	Calibrated
Gyroscope	Calibrated
Strapdown Integration (SDI)	Yes
Gyroscope	
Standard full range	2000 deg/s
In-run bias stability	8 deg/h
Bandwidth (-3dB)	520 Hz
Noise Density	0.007 ⁰/s/√Hz
g-sensitivity (calibr.)	0.001 º/s/g
Accelerometer	
Standard full range	10 g
In-run bias stability	10 (x,y) 15(z) µg
Bandwidth (-3dB)	500 Hz
Noise Density	60 µg/√Hz
Magnetometer	
Standard full range	+/- 8 G
Total RMS noise	1 mG
Non-linearity	0.2%
Resolution	0.25 mG
GNSS Receiver	
Brand	n/a
Model	n/a
RTCM input port	n/a
Barometer	
Standard full range	300-1250 hPa



- White label and OEM integration options available
- 3D models available on request
- Available at DigiKey, Mouser, Farnell, Arrow and local distributors

Mechanical		
IP-rating	IP51	
Operating Temperature	-40 to 85 °C	
Casing material	PC-ABS	
Mounting orientation	No restriction, full 360° in all axes	
Dimensions	28x31.5x13 mm	
Connector	Main: Phoenix Contact 16 pin, 1.27 mm pitch	
Weight	8.9 g	
Certifications	CE, FCC, RoHS	
Electrical		
Input voltage	4.5 to 24V	
Power consumption (typ)	<1 W	
Interfaces / IO		
Interfaces	UART, CAN, RS232	
Sync Options	SyncIn, SyncOut, ClockSync	
Protocols	Xbus, ASCII (NMEA) or CAN	
Clock drift	10 ppm (or external)	
Output Frequency	Up to 2kHz, 400Hz SDI	
Built-in-self test	Gyr, Acc, Mag, Baro	
Software Suite		
GUI (Windows/Linux)	MT Manager Firmware updater,	
	Magnetic Field Mapper	
SDK (Example code)	C++, C#, Python, Matlab, Nucleo,	
	public source code	
Drivers	LabVIEW, ROS, GO	
Support	BASE by XSENS: online manuals,	
	community and knowledge base	



Total RMS noise

Relative accuracy



Unless stated otherwise, all specifications are typical. Specifications subject to change without notice.

1.2 Pa

+/- 8 Pa (~0.5m)