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Devyatisilny A.S. (devyatis@dvo.ru), **Shurygin A.V.**

Institute of Automation and Control Processes

MATHEMATICAL MODELS OF TRAJECTORY PARAMETERS OF MOBILE OBJECTS FOR EMBEDDED GLONASS SYSTEMS

The article is devoted to the problem of expanding the on-board GLONASS. It presents a mathematical model of the corresponding inverse trajectory problem, describes the technology, covers a research, and proposes procedures for increasing the solvability of the problem under the finite accuracy of measurement and numeration in a computing environment. To solve the problem, we proposed a neural-like algorithm of the Kalman type. The results of computational experiments are also presented here.

Keywords: navigation satellite system, GLONASS, inverse trajectory problem, model, motion, velocity, neural-like algorithm.

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