CLAIMS

1. A correction method for a gyro sensor which measures angular velocity of a vehicle about an axis in a vertical direction, comprising:

a generation process of performing a process on a difference between a measured azimuth obtained by performing a process on an sensor output, which is an output from the gyro sensor, and a vehicle azimuth estimated by using markers arranged along a traveling road of the vehicle to obtain correction information; and

a correction process of correcting the sensor output or the measured azimuth by using the correction information;

wherein the correction information is information indicating a temporal change of the difference, and

the correction process is a process of correcting the sensor output or the measured azimuth with a correction amount based on the correction information;

wherein the correction information includes at least a gradient a of a straight line approximating the temporal change of the difference, and

the correction process is a process of shifting the output from the gyro sensor by the correction amount corresponding to the gradient a.

2. A correction method for a gyro sensor which measures angular velocity of a vehicle about an axis in a vertical direction, comprising:

a generation process of performing a process on a difference between a measured azimuth obtained by performing a process on an sensor output, which is an output from the gyro sensor, and a vehicle azimuth estimated by using markers arranged along a traveling road of the vehicle to obtain correction information; and

a correction process of correcting the sensor output or the

measured azimuth by using the correction information;

wherein the correction information is information indicating a temporal change of the difference, and

the correction process is a process of correcting the sensor output or the measured azimuth with a correction amount based on the correction information;

wherein the correction information includes at least a gradient a and an intercept b of a straight line approximating the temporal change of the difference, and

the correction process is a process of shifting the measured azimuth by the correction amount obtained by multiplying a value of the gradient a by an elapsed time T from a starting point of the temporal change of the difference and adding a value of the intercept b.

~~2. The correction method for the gyro sensor in claim 1, wherein the correction information is information indicating a temporal change of the difference, and~~

~~the correction process is a process of correcting the sensor output or the measured azimuth with a correction amount based on the correction information.~~

~~3. The correction method for the gyro sensor in claim 2, wherein the correction information includes at least a gradient a of a straight line approximating the temporal change of the difference, and~~

~~the correction process is a process of shifting the output from the gyro sensor by the correction amount corresponding to the gradient a.~~

~~4. The correction method for the gyro sensor in claim 2, wherein the correction information includes at least a gradient a and an~~

~~intercept b of a straight line approximating the temporal change of the difference, and~~

~~the correction process is a process of shifting the measured azimuth by the correction amount obtained by multiplying a value of the gradient a by an elapsed time T from a starting point of the temporal change of the difference and adding a value of the intercept b.~~

~~5. The correction method for the gyro sensor in claim 1, wherein the correction information is a temporal average value of the difference, and~~

~~the correction process is a process of shifting the measured azimuth by a correction amount corresponding to the temporal average value of the difference.~~

3~~6~~. The correction method for the gyro sensor in ~~any one of claims 1 to 5~~claim 1 or claim 2, comprising:

a lateral shift amount detection process of detecting a lateral shift amount of the vehicle with respect to each of the markers; and

an azimuth estimation process of estimating the vehicle azimuth based on lateral shift amounts detected by the lateral shift amount detection process for at least two of the markers.

4~~7~~. The correction method for the gyro sensor in claim 3~~6~~, comprising an azimuth information obtaining process of obtaining, from an information providing part provided for providing azimuth information which can identify a direction of a line segment connecting two of the markers or a direction of the traveling road, the azimuth information, wherein

in the azimuth estimation process, the vehicle azimuth is estimated with reference to a direction identified by the azimuth

information.

5~~8~~. The correction method for the gyro sensor in claim 4~~7~~, wherein the information providing part is a wireless tag attached to the each of the markers.