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.

3. The correction method for the gyro sensor in 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. The correction method for the gyro sensor in claim 3, 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. The correction method for the gyro sensor in claim 4, wherein the information providing part is a wireless tag attached to the each of the markers.