vector is constrained by the velocity of the mobile object and the clock drift is constrained by a constraint condition that a time variation of the clock drift is linear.

3. The travel distance estimation device according to claim 1 or 2, further comprising:

an estimated orientation determination unit that successively determines a traveling orientation of the movable object; and

a position determination unit that, based on the estimated travel distance calculated by the travel distance calculation unit and the traveling orientation determined by the estimated orientation determination unit, successively determines a relative position of the movable object relative to a position determined the previous time,

wherein

upon recalculating by the travel distance correction unit the estimated travel distance, the position determination unit recalculates, based on the recalculated estimated travel distance and the traveling orientation determined by the estimated orientation determination unit, a relative position of the movable object after the velocity initial value was determined by the initial setting value determination unit the previous time until the velocity initial value is determined by the initial setting value determination unit this time.

4. The travel distance estimation device according to any one of claims 1 to 3, wherein

assuming a linear increase in errors of the pre-correction past estimated velocities, the past velocity correction unit determines the corrected past velocity this time by correcting each of the pre-correction past estimated