Anemometer position from GNSS, IMU, barometer, magnetometer
\( x_{\text{anemo}}, y_{\text{anemo}}, z_{\text{anemo}} \) (TRS)

Relative wind speed from sonic anemometer
\( u_{\text{anemo}}, v_{\text{anemo}}, w_{\text{anemo}} \) (BFRS)

Induced flow from roll and pitch gyroscope and the distance COM <-> anemometer
\( u_{\text{induced}}, v_{\text{induced}} \) (BFRS)

UAV groundspeed from EKF2
\( u_{\text{UAV}}, v_{\text{UAV}}, w_{\text{UAV}} \) (TRS)

UAV attitude from EKF2
\( \psi, \phi, \theta \) (BFRS)

Measurement location
\( N, E, D \) (TRS)

Time and space resolved wind speed (TRS)

Wind speed
\( W-E, S-N, U-D \) (TRS)