1. Restricted expression of the title of this paper should be reorganized. Try to focus on your novel research.

2. Please double-check that all abbreviations appearing for the first time have been described before or have not been described repeatedly. For instance, GEDO CE?

3. I have some puzzles about the pre-calibration between the GNSS and part of the inertial navigation parameters in an area of good GNSS signal. Why emphasize that it must be carried out in a straight track area? How long distance is the straight track segment required for calibration? Is it appropriate if there is a slight curvature change? Can the pre-verified parameters avoid the cumulative error divergence of the later inertial navigation system?

4. Due to the use of GNSS for prior verification, is the statement about GNSS-denied appropriate in this paper?

5. Is the inertial navigation system used in Table 2 based on a single-axis gyroscope or a three-axis gyroscope?

6. Please add an analysis assessment in the experimental part to clarify the theoretical advantages described in parts of 2.5.1 and 2.5.2.

7. What is the difference between the two examples for the test of the proposed theoretical method? Is it just a scene change or a distributed verification or something else?