



New connection on: : 18-04-2018 : 21:08:58 - Last disconnection on: : 18-04-2018 : 20:51:07

V 4.0.0.44358(LP,U,linux) (Rev:43856 2017-04-27 09:03:29 +0200#(D201802)) (RPM D201802)

Welcome to EPOQUE Rebuild under the Production Environment

[EPODOC: SS 29] imu and non-orthogonal

Results in EPODOC 0

EPODOC: term 'NON-ORTHOGONAL' not found in index 'BI'. *WARNING(1)*

[SS 30] imu and non_orthogonal

Results in EPODOC 0

[SS 31] imu and non 2d orthogonal

Different expressions or operators have been used without brackets. *ERROR(-50002)*

[SS 31] imu and (non 2d orthogonal)

Results in EPODOC 0

[SS 32] non 2d orthogonal

Results in EPODOC 2.340

[SS 33] 32 and inertial and system

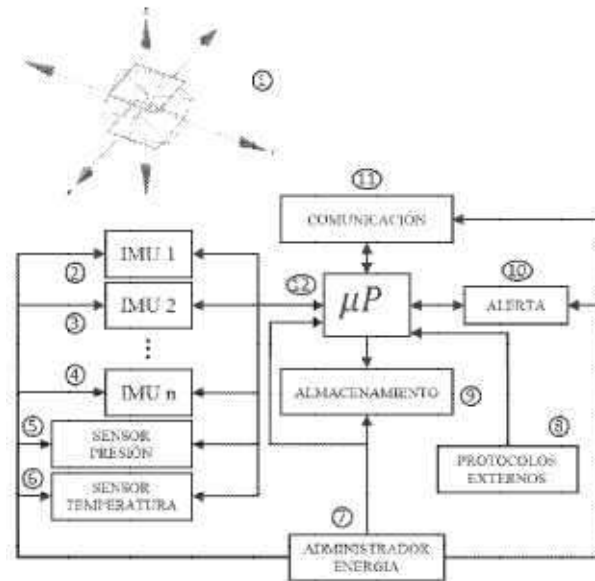
Results in EPODOC 8

[SS 34] ..li pn ti



PN - [WO2017163108](#) A1 20170928

TI - **SYSTEM** FOR TRACKING ANIMATE OR INANIMATE OBJECTS IN REAL TIME WITH AUTOREFERENCING, AUTOCALIBRATION AND ROBUST SYNCHRONISATION



- 5 PRESSURE SENSOR
- 6 TEMPERATURE SENSOR
- 7 POWER MANAGER
- 8 EXTERNAL PROTOCOLS
- 9 STORAGE
- 10 ALERT
- 11 COMMUNICATION

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PN - [CN106855409](#) A 20170616

TI - Four-gyro four-accelerometer **non-orthogonal** oblique arrangement table structure

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PN - [US2016327926](#) A1 20161110

TI - (A1)

Non-Orthogonal Six-Rod Satellite Communication in Motion Servo **System** and Control Method

- (B2)

Non-orthogonal six-rod satellite communication in motion servo **system** and control method

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PN - [WO2015180229](#) A1 20151203

TI - **NON-ORTHOGONAL SIX-ROD SATELLITE COMMUNICATION IN MOTION SERVO SYSTEM AND CONTROL METHOD**

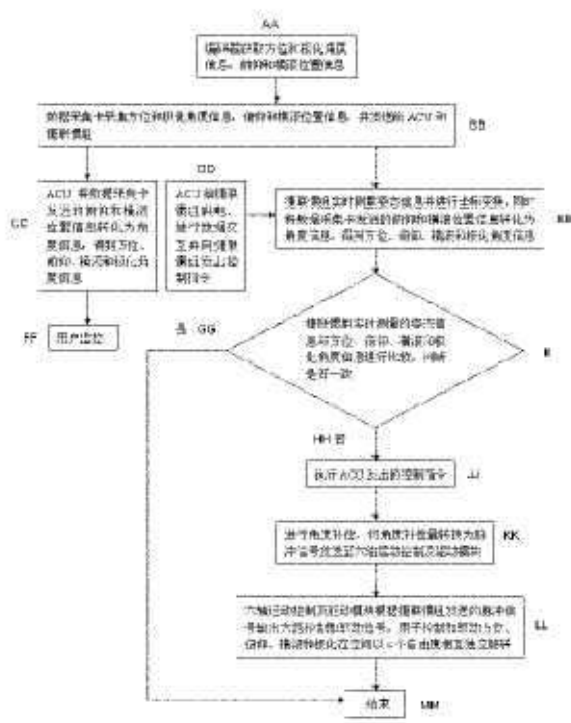


图 2 / FIG. 2

- AA AN ENCODER ACQUIRES AZIMUTH AND POLARIZATION ANGLE INFORMATION, AND PITCH AND ROLL POSITION INFORMATION.
- BB A DATA COLLECTION CARD COLLECTS THE AZIMUTH AND POLARIZATION ANGLE INFORMATION AND THE PITCH AND ROLL POSITION INFORMATION, AND SENDS SAME TO AN ACU AND A STRAPDOWN INERTIAL MEASUREMENT UNIT.
- CC THE ACU CONVERTS THE PITCH AND ROLL POSITION INFORMATION SENT BY THE DATA COLLECTION CARD INTO ANGLE INFORMATION TO OBTAIN AZIMUTH, PITCH, ROLL AND POLARIZATION ANGLE INFORMATION.
- DD THE ACU SUPPLIES POWER TO THE STRAPDOWN INERTIAL MEASUREMENT UNIT, PERFORMS DATA INTERACTION AND SENDS OUT A CONTROL INSTRUCTION TO THE STRAPDOWN INERTIAL MEASUREMENT UNIT.
- EE THE STRAPDOWN INERTIAL MEASUREMENT UNIT MEASURES POSTURE INFORMATION AND PERFORMS COORDINATE TRANSFORMATION IN REAL TIME, AND AT THE SAME TIME, CONVERTS THE PITCH AND ROLL POSITION INFORMATION SENT BY THE DATA COLLECTION CARD INTO THE ANGLE INFORMATION TO OBTAIN AZIMUTH, PITCH, ROLL AND POLARIZATION ANGLE INFORMATION.
- FF USER MONITORING.
- GG YES.
- HH NO.
- II THE POSTURE INFORMATION MEASURED IN REAL TIME BY THE STRAPDOWN INERTIAL MEASUREMENT UNIT IS COMPARED WITH THE AZIMUTH, PITCH, ROLL AND POLARIZATION ANGLE INFORMATION TO JUDGE WHETHER THEY ARE CONSISTENT.
- JJ THE CONTROL INSTRUCTION SENT OUT BY THE ACU IS EXECUTED.
- KK ANGLE COMPENSATION IS PERFORMED, AND THE ANGLE COMPENSATION AMOUNT IS CONVERTED INTO A PULSE SIGNAL TO BE SENT TO A SIX-AXIS MOVEMENT CONTROL AND DRIVE MODULE.
- LL THE SIX-AXIS MOVEMENT CONTROL AND DRIVE MODULE OUTPUTS SIX-AXIS CONTROL AND DRIVE SIGNALS FOR CONTROLLING AND DRIVING AZIMUTH, PITCH, ROLL AND POLARIZATION TO MUTUALLY ROTATE INDEPENDENTLY IN FOUR FREEDOM DEGREES IN A SPACE ACCORDING TO THE PULSE SIGNAL SENT BY THE STRAPDOWN INERTIAL MEASUREMENT UNIT.
- MM END.

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PN - [EP3088981](#) A1 20161102

TI - (A1 A4)
NON-ORTHOGONAL SIX-ROD SATELLITE COMMUNICATION IN MOTION SERVO SYSTEM AND CONTROL METHOD

6/8 © EPODOC / EPO
PN - [CN104133432](#) A 20141105

TI - (A)
Non-orthogonal six-bar satellite communication in motion servo **system** and control method

7/8 © EPODOC / EPO

PN - [CN103234560](#) A 20130807

TI - (A)
Zero calibration method for strapdown **inertial** navigation **system**

8/8 © EPODOC / EPO

PN - [CN102116629](#) A 20110706

TI - Method of configuring six micro mechanical electronic gyros based on regular tetrahedron

[SS 34]