



New connection on: : 03-12-2020 : 18:02:43 - Last disconnection on: :
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Welcome to EPOQUE Rebuild under the Production Environment

[EPODOC: SS 31] trajector+ and simulat+ and radar and vehicle and (UAV or drone)

Results in EPODOC 0

[SS 32] UAV or drone

Results in EPODOC 17.826

[SS 33] 32 and trajector+ and simulat+

Results in EPODOC 9

[SS 34] 33 and radar

Results in EPODOC 1

[SS 35] ..li



1/1 © EPODOC / EPO

PN - [EP3296760](#) A1 20180321

PR - IT20160094409 20160920

AP - [EP20170192256](#) 20170920

DT - *; Rep

CT - || STSE (A1)

[US5164734](#) A 19921117 [A] (FREDERICKS DUANE G [US], et al)

[A] 1-14

* column 1, line 48 - column 2, line 9 *

* column 3, line 4 - column 3, line 11 *

* column 7, line 45 - line 63 *

* column 10, line 57 - line 68 *

* column 13, line 23 - column 14, line 29 *

* figures 1, 3, 7, 8 *;

[US2016088498](#) A1 20160324 [A] (SHARAWI MOHAMMAD S [SA])

[A] 1-14

* abstract *

* paragraph [0004] - paragraph [0006] *

* paragraph [0014] - paragraph [0015] *

** paragraph [0029] **

** figure 1 *;*

[US2005128136](#) A1 20050616 [A] (WITTENBERG PETER S [US], et al)

[A] 1-14

** abstract **

** figure 1 *;*

[WO2018011077](#) A1 20180118 [E] (QINETIQ LTD [GB])

[E] 1-5,7-9,11,13,14

** page 6, line 1 - page 8, line 12 **

** page 9, line 13 - page 10, line 12 **

** figures 1-3 **

CCI - [G01R29/10](#) ; [G01S7/40](#)

CI - G01R29/10 (EP)

- G01S7/40 (EP)

PA - LEONARDO SPA [IT]

TI - METHOD AND SYSTEM FOR TESTING **RADAR** SYSTEMS

AB - The invention concerns a method and system for testing **radar** systems' capability to detect and track targets. In particular, the method comprises defining a first non-linear **trajectory** of a non-linear moving target to be **simulated**, wherein said first non-linear **trajectory** comprises a sequence of first positions, each defined by respective range, azimuth and elevation with respect to an antenna (1) of a **radar** system under test. The method further includes computing a second non-linear **trajectory** based on the first non-linear **trajectory**. Said second non-linear **trajectory** comprises a sequence of second positions, each of which is defined by respective range, azimuth and elevation with respect to the antenna (1) of the **radar** system under test, is associated with a corresponding first position defined, with respect to the antenna (1) of the **radar** system under test, by the same azimuth and elevation as said second position and by a greater range than said second position, and is associated with a corresponding time at which the non-linear moving target is located at the corresponding first position associated with said second position. The method further includes: providing a **drone** (21) equipped with an on-board antenna (212) for receiving **radar** signals transmitted by the antenna (1) of the **radar** system under test; and flying the **drone** (21) by following the second non-linear **trajectory** and by causing said **drone** (21) to be located at each second position at the corresponding time associated with said second position. Additionally, the method includes also: when the **drone** (21) is located at one of the second positions, processing an incoming **radar** signal received by the on-board antenna (212) at said second position so as to generate a processed **radar** signal **simulating** a **radar** echo from the non-linear moving target located at the corresponding first position associated with said second position, and transmitting the processed **radar** signal by the on-board antenna (212) from said second position towards the antenna (1) of the **radar** system under test.