EXPERIMENTAL EVALUATION
OF A
THRUST VECTOR LOAD CELL

R. W. Postma
Rocketdyne

November 1970

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FOREWORD

The work presented herein was sponsored by Arnold Engineering Development Center (AEDC), Air Force Systems Command (AFSC), Arnold Air Force Station, Tennessee, under Program Element 65701F, Project 4344, Task 37.

This report was prepared by the Research Division of Rocketdyne, a Division of North American Rockwell Corporation, Canoga Park, California, under Air Force Contract F40600-70-C-0007, "Research Contract for the Evaluation of a Thrust Vector Load Cell." The contract consisted of the instrumentation and calibration of a half-scale model previously fabricated and partially strain gaged under Contract F40600-68-C-0004, "Research of a Vector Thrust Load Cell," Report No. AEDC-TR-64-233. Inclusive dates of the present evaluation were November 1969 to February 1970. This report has been designated R-8254 by Rocketdyne. The manuscript was submitted for publication 15 June 1970.

The author is particularly indebted to J. LeFevere and others associated with the NAR Tri-Sonic Wind Tunnel Facility who provided invaluable advice and assistance in the calibration of the model.

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This technical report has been reviewed and is approved.

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ABSTRACT

This report describes the results of an experimental evaluation of a half-scale (physical size) model of a previously analyzed six-component force balance for testing rocket engines. The force range of the model was scaled down from 5000 lbf to 200 lbf, and structural parameters were scaled to represent those of the full-scale version which was analyzed under Contract F40600-68-C-0004. The evaluation includes the determination of (1) first- and second-order interactions of single and combination loads and (2) the effect of combination loads at expected gimbal points for typical rocket engines. The data which are presented in tabulated form, validate the prior analysis, and demonstrate that short force measuring links, assembled into a compact integral structure, do not result in excessive interactions.
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SECTION I

SUMMARY

This evaluation of a scale model vector thrust load cell has served to validate the analytical study of the concept of using an integral force balance for measuring rocket engine thrust. The precision of the model demonstrated capability to exceed the $1/3^\circ$ vector angle final accuracy goal by an order of magnitude and readily achieve the 0.020-inch vector location and 1/2 percent thrust amplitude accuracy goals of the preceding contract.

The basic structure of the design tested showed that it is feasible to build a balance comprised of short, rigid force-measuring links assembled into a compact structure located at the front of the rocket motor. The balance tested in this program was purposely designed to demonstrate the capability to achieve low interactions between the axial force links and the side force links. The design was intentionally kept elementary so as to make its understanding and analysis as simple as possible.

Having demonstrated these objectives, it is worthwhile to reflect on the importance of low interactions. Although such qualities as low interaction and linearity are the usual criteria for a successful six-component force balance, accurate results can be achieved if relatively large first-order interactions and non-linearities are repeatable, can be accurately evaluated by proper calibration, and can be corrected for in the reduction of test data. From a practical point of view, second-order interactions caused by balance distortion under load should be small because many combinations of calibration
loads are needed to evaluate them. The second-order interactions in this testing were demonstrated to be insignificant as predicted by the previous analysis.

In contrast to other balance geometries analyzed in the previous study (Ref. 1), it is a characteristic of the balance design tested that the precision of vector location depends primarily on force link precision rather than on the structural geometry. The precision achieved during this testing did not reach the ultimate precision capabilities of high precision load cells or wind tunnel balances although the vector location and magnitude precision were well within the objectives of this program. As discussed in the preceding study, important factors in this concept are (1) the convenience of being able to evaluate interactions on the special calibration rig prior to aligning the balance to the engine, (2) the ability to assemble the balance and engine on the test stand, and (3) the ability to perform final calibrations before and after test firing. As discussed in the section on results, the improvement of force cell precision is partly a matter of reducing strain-gage creep and further refinement of calibration technique.
SECTION II

INTRODUCTION

In rocket engine development and production acceptance static testing it is frequently essential that the magnitude, direction, and location of the net thrust vector be determined. This is currently accomplished through use of multi-component thrust stands comprised of externally arranged load-measuring assemblies. Because of the obvious operational short-comings of such arrangements, the idea of a single transducer which could be used to obtain thrust vector data has long been attractive. But there was little progress toward achieving such a device until the Arnold Engineering Development Center sponsored the analytical evaluation of the concept in 1968 under Contract F40600-68-C-0004.

The conclusions from this study (Ref. 1) indicated that a vector thrust load cell with an integral propellant compensator is capable of providing the general advantages of:

1. Reduced on-site calibration effort
2. Simplified alignment of the rocket engines
3. Improved thrust measurement accuracy for liquid propellant rockets.

Because of the unorthodox force link geometries, the short force link lengths, and the stiff flexures and force links that were incorporated in the basic concept analyzed; an experimental evaluation of a model transducer was recommended. This report describes the experimental program which was carried out to confirm the analytical conclusions.
SECTION III

DESCRIPTION OF APPARATUS

3.1 MODEL CELL

A thrust cell for use over a range of 1000 to 20,000 pounds of axial force at vector angles up to 12° was considered for the analytical study. A model cell (Fig. 1) based on the following design and scaling considerations, was completed and used for the experimental evaluation.

1. The dimensions which establish kinematic relationships are half of those specified for the full-scale basic design. These dimensions are lengths of force links, positions of force links, and plate diameter. The overall size of the model is 7-1/8 inches diameter by 3-3/4 inches.

2. Load capacity was scaled down 25:1. Nominal axial thrust capacity of the model is 200 lbf compared to 5000 lbf and side thrust capacity of 40 lbf compared to 1000 lbf.

3. The reduced load capacity allowed use of flexures machined as two short small diameter rods near the end of each force link. Because each of these rod flexures provides three degrees of freedom, the total number of flexures is reduced in the ratio of 5:2 compared to the full-scale design (where four circular flexures and one cruciform torsion flexure are needed per force link).
4. Restoring moments caused by bending and torsion of the rod flexures are approximately the same percentage of applied forces as the circular arc flexures used in the full-scale design. Because rod flexures are much stiffer in bending than circular arc flexures, the reduced loads were necessary to allow the cross-sectional areas of the rods to be scaled down. The result is that the relative bending stiffness (also referred to as percentage redundancy) of the half-scale model is the same as the full-scale design.

5. Non-linear, second-order interactions are also designed to be the same as in the full-scale version. Consequently, angular distortion of the balance under nominal load is the same. To accomplish this, compression and tension deflections of flexures and force cells, machined as part of each force link, are scaled to one-half at nominal load (approximately 0.001 inch vs. 0.002 inch). The thickness of the two circular plates and the size of brackets supporting side force links were also scaled so that calculated plate and bracket deflections are reduced to one-half at nominal loads.

6. Force cells, as well as flexures, were machined as integral parts of the force links. The force cells are short columns with "I" cross sections that are strained in compression or tension. Strain gages can be bonded to either the webs or the outsides of the flanges of the axial force cells ($L_1$, $L_2$, and $L_3$). The side force cells have sufficient space for strain gages on the flanges only.
7. The force links, plates, and brackets were machined from 17-4 PH corrosion-resistant steel, the same material which would be used for a full-scale working model. Force links were age-hardened after partial machining to achieve the high yield strength needed for repeatable stress-strain characteristics in force cells and flexures.

8. Semi-conductor strain gages were bonded to the three axial force links, $L_1$, $L_2$, and $L_3$ (Fig. 2) and the side force link, $L_4$. These strain gages were wired into Wheatstone bridge circuits and temperature compensated as usual.

9. The alignment of the axial load and side load to the reference plane was controlled by the use of precision levels. The precision of the level used to align the space of the cell has a resolution of .00002 radians. The level used to align the axial force rod has a resolution of .00008 radians. During the application of loads to the balance, the base of the balance was realigned by observing these two levels to compensate for balance and support deflections.

3.2 CALIBRATION RIG

The calibration rig used for this work is the wind tunnel balance certification equipment at the North American Rockwell Corporation, Los Angeles Division, Tri-Sonic Wind Tunnel. In addition to the high precision alignment fixtures, this system has digital readout instruments for use with strain gages.

The model cell is shown mounted on the movable sling of the calibration rig in Fig. 3.
SECTION IV  
CALIBRATION AND DATA REDUCTION PROCEDURES

Calibration constants including correction terms for first-order interactions were obtained by applying loads directly in line with the four strain-gaged force links (L₁, L₂, L₃, and L₄ of Fig. 1).

The data reduction was accomplished using existing computer programs at the Tri-Sonic Wind Tunnel. Least squares second-degree best-fit curves were obtained for the primary constants and first-degree curves for the interaction terms. For loadings at other points than the four force links, pseudo reaction forces at the four calibration load stations were obtained from the following equations.

\[
R_1 = (B_{11}E_1 + C_{11}E_1^2) + M_{12}R_2 + M_{13}R_3 + M_{14}R_4
\]

\[
R_2 = M_{21}R_1 + (B_{22}E_2 + C_{22}E_2^2) + M_{23}R_3 + M_{24}R_4
\]

\[
R_3 = M_{31}R_1 + M_{32}R_2 + (B_{33}E_3 + C_{33}E_3^2) + M_{34}R_4
\]

\[
R_4 = M_{41}R_1 + M_{42}R_2 + M_{43}R_3 + (B_{44}E_4 + C_{44}E_4^2)
\]

In these equations the \(R_i\) terms are forces at the four load stations in line with the force links, and the \(E_i\) terms are the electrical outputs in millivolts. The \(B_{ii}\) and \(C_{ii}\) terms are constants describing the calibration curves obtained from calibration loads over the respective force link \(L_i\) (lb-volts/mv and lb-volts²/mv² respectively). The \(M_{ij}\) terms are considered

---

\(^1\)The reaction forces may be considered to exist at these points although the input forces are reacted at the actual force link locations.
to be interaction terms with reference to these four load stations (lb/lb).

These terms represent the partial derivatives of applied calibration force
to the apparent force indicated at another load station and are computed
from the calibration data by:

\[ M_{ij} = \frac{B_{ij}}{B_{ij}} \]  

Here the \( B_{ij} \) terms are the interaction slopes from the calibrations in
lb-volts/mv.

Since the objective of the data reduction is to compute the magnitude,
direction, and location of the external force vector, another set of equations
is written to translate the pseudo-reaction forces obtained by solution of the
preceding equations for cases where an axial load at the center is combined
with a side load at some known distance from the center of the balance. The
first set of equations was solved by iteration, using the standard computer
program and the resulting reaction forces were entered into the following set
of equations:

\[ F_z = R_1 + R_2 + R_3 \]
\[ F_x = R_4 \]
\[ M_y = R_1 x_1 + R_2 x_2 + R_3 x_3 \]
\[ F = \sqrt{\frac{2}{F_x} + \frac{2}{F_z}} \]
\[ \theta = \text{arc tan} \left( \frac{F_x}{F_z} \right) \]
\[ X = \frac{M_y}{F_z} \]
By this method the strain gage voltages $E_i$ produced by known input forces $F_z$ and $F_x$ have been used to compute reaction forces $R_i$ at the calibration load stations which are then translated to the calculated external thrust vector for comparison with the known thrust vector.
5.1 CALIBRATION CONSTANTS

The calibration constants obtained in this experiment are given in Table I in matrix form.

<table>
<thead>
<tr>
<th>$B_{11}$</th>
<th>$M_{12}$</th>
<th>$M_{13}$</th>
<th>$M_{14}$</th>
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<tr>
<td>-11.6408</td>
<td>.00723</td>
<td>-.00243</td>
<td>.000017</td>
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<td>$C_{11}$</td>
<td>.01191</td>
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<table>
<thead>
<tr>
<th>$M_{21}$</th>
<th>$B_{22}$</th>
<th>$M_{23}$</th>
<th>$M_{24}$</th>
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<tr>
<td>-.00657</td>
<td>-13.2367</td>
<td>-.00489</td>
<td>.001386</td>
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<tr>
<td>$C_{22}$</td>
<td>.01642</td>
<td></td>
<td></td>
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<table>
<thead>
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<th>$M_{32}$</th>
<th>$B_{33}$</th>
<th>$M_{34}$</th>
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<tr>
<td>.00301</td>
<td>.00731</td>
<td>-12.1871</td>
<td>.001496</td>
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<tr>
<td>$C_{33}$</td>
<td>.01444</td>
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<table>
<thead>
<tr>
<th>$M_{41}$</th>
<th>$M_{42}$</th>
<th>$M_{43}$</th>
<th>$B_{44}$</th>
</tr>
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<tbody>
<tr>
<td>.000269</td>
<td>.000418</td>
<td>.000260</td>
<td>11.5535</td>
</tr>
<tr>
<td>$C_{44}$</td>
<td>.00375</td>
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</table>
5.2 TABULATED RESULTS

Table II compares the measured values of thrust vector magnitude angle and location (corrected for first-order interactions from Table I) with the calibration inputs of the same parameters.
SECTION VI
DISCUSSION OF RESULTS

6.1 ANGULAR PRECISION

The experimental results satisfactorily accomplished the main objective of this program: that of evaluating the basic design described as the orthogonal tripod geometry in Ref. 1. Most noteworthy, the first-order interactions resulting from force link misalignment were very small and were readily corrected for as a routine procedure in data reduction. Also, the second-order interactions caused by angular distortion of force links under load were sufficiently small that very high angular precision was achieved by accounting for only the first-order interactions. The angular measurements would still have been very precise if the first-order interactions were also ignored.

The interaction caused by misalignment of the axial force links (see Section 7.2.1, Ref. 1) is given by the sum of $M_4 + M_5 + M_6$ in the calibration matrix (Table I) which is equal to .0003 radians for a purely axial load. The results corrected for this interaction (shown in Table II) gave a $2\sigma$ error of .00016 radian for all purely axial loads ($\theta = 0$) and .00036 radian for all load combinations including angles up to $22^\circ$ of arc. The maximum error as shown in the tabulated results in Table II was .00047 radian at $11.5^\circ$.

During the combination load tests the side loads were applied at a station representing a typical gimbal location. This location of $z = 6.255$ inches from the center of the balance would be equivalent to $12.510$ inches in a full-scale model.

$2$Twice the standard deviation represents a probability of .95 that an individual error will be less than the $2\sigma$ error (for large sample uses). This is sometimes stated as the 95% confidence level.
### Table II

**Results (Corrected For First Order Interactions)**

<table>
<thead>
<tr>
<th>Beam</th>
<th>Fx (lbf)</th>
<th>Fy (lbf)</th>
<th>Angle (degrees)</th>
<th>Location (in)</th>
<th>Measured Force (lbf)</th>
<th>Measured Angle (degrees)</th>
<th>Force Adjusted For BIAS</th>
</tr>
</thead>
<tbody>
<tr>
<td>12</td>
<td>100</td>
<td>0</td>
<td>0.0008</td>
<td>-0.0008</td>
<td>20.65</td>
<td>0.0018</td>
<td>-0.0008</td>
</tr>
<tr>
<td>100</td>
<td>0</td>
<td>0</td>
<td>0.0008</td>
<td>-0.0008</td>
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<td>0.0018</td>
<td>-0.0008</td>
</tr>
<tr>
<td>200</td>
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<td>0</td>
<td>0.0008</td>
<td>-0.0008</td>
<td>20.65</td>
<td>0.0018</td>
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</tr>
<tr>
<td>300</td>
<td>0</td>
<td>0</td>
<td>0.0008</td>
<td>-0.0008</td>
<td>20.65</td>
<td>0.0018</td>
<td>-0.0008</td>
</tr>
<tr>
<td>400</td>
<td>0</td>
<td>0</td>
<td>0.0008</td>
<td>-0.0008</td>
<td>20.65</td>
<td>0.0018</td>
<td>-0.0008</td>
</tr>
</tbody>
</table>

The remaining data were taken on the following day. Calibrations over force lines \( F_x \) and \( F_y \) were performed in Runs 13, 14, and 15 of the preceding day.

### Footnotes:
- *Error in data reduction.
- f Force link \( F_y \) was loaded in tension on this loading, which was beyond the range of the calibrations unless specified in the data reduction.
- f These loads at \( f = 9.928 \) are beyond the normal range of the balance.

15/16
One of the primary questions to be answered in this evaluation was whether or not the side load could be accurately measured when applied at the distance \( z \) from the side force link. The results verify the analysis in Ref. 1 and show conclusively that the effect of this overhung loading structure is very minimal. In Runs 18, 19, and 20 (Table II) the additional error due to the increase in vector angle from 0 to 11.5° is small enough that the second-order interactions caused by balance distortion (see Section 7.3, Reference 1) can be easily ignored except by the most exacting requirements. The second-order interaction in Run 20 for a vector angle of 11.5° at the nominal axial load of 200 pounds was .00024 radian which agreed closely with the value of .00021 radian predicted for the basic design on Page 56 of Reference 1.

6.2 PRECISION OF THRUST MAGNITUDE

The precision of the strain gaged force links was adequate for the primary purpose of this experiment, which was to evaluate the structural geometry of the basic design. As shown in Table II, the 2σ precision of the resultant thrust for all combinations of axial and side loads was 0.14 percent. The semiconductor strain gages evidenced a slight amount of creep under load (.03 percent for the first minute of loading for the axial force links). For this reason and because of the limited time available for the completion of the required number of tests, data was taken between one and two minutes after application of load, which did not always allow sufficient time for the weight pans to stop swinging. Generally, a calibration of this nature takes about two weeks including set-up time and re-runs, and undoubtedly the precision of the data shown in Table II, which was taken in the final two days of a five-day period, could have been improved had more time been available to improve calibration technique.
Under stress, creep of the epoxy bond between the strain gage and the substrate is always a potential problem in the manufacture of strain gage transducers. Metal foil strain gages are less subject to this effect than semiconductor gages because of the relative thickness of the constantan foil (.0001 inch compared to the silicon sliver, .0005 inch). However, semiconductor load cells are sufficiently free from creep if long gages are used and if proper attention is paid to the stress distribution along the strain gage. Given proper attention to these details, creep from semiconductor strain gages would be about .05 percent in five minutes. Creep from constantan foil strain gages would be typically about .01 percent in the same period of time.

The strain gages used on the axial force links were somewhat non-linear as evidenced by the second-degree constants in the matrix in Table I (C_{11}, C_{22}, and C_{33}). This presented no problem since the method of data reduction provided for a second degree nonlinearity. The semiconductor gages used on the side force link were more linear as shown by the relative size of C_{44} to B_{44}. The nonlinearity may be calculated by 1/2 (EC/B) which is 0.11 percent of full scale for the side force link.

The first-order interaction of the side force link on axial force was reasonably small. This interaction is primarily caused by misalignment of the side force link as explained in Section 7.2.2., Ref. 1. This interaction is equal to M_{14} + M_{24} + M_{34} (Table I) and is also equal to .0028 Fx/Fz. The maximum value of this would be 0.056 percent at a 11.5° vector angle. Again, this interaction was readily extracted from the data.

---

3Conversation by the author with John Pugnaire, Bytrex Division of Tyco Corp., Waltham, Mass.
6.3 PRECISION OF VECTOR LOCATION

Since the forces resolved by the three axial force links determine the location of the thrust vector in the xy plane of the balance, force link precision directly affects the precision of the measured vector location (see Section 7.1, Ref. 1). Consequently, the comments in the preceding paragraphs regarding precision also apply here. The precision obtained for the location of the thrust vector given in terms of the measured bias, and the 2σ variation of the vector location data in the last column of Table II was \(-0.0024 \text{ inch} \pm 0.0003 \text{ inch}\).

Certain adjustments were made in the presentation of this data. After Run 18 it was noticed that the flexure connecting the axial force rod to the balance was bent. At this point a new flexure was installed and as a consequence the location bias was reduced by 0.008 inch. The second column for location error in Runs 12, 17, and 18, Table II, show this correction. After this adjustment the average of all runs (excluding 25 and 26) was \(-0.0024 \text{ inch}\) which can be partially attributed to errors in the measurement of the location of the three load stations \((x_1, x_2, \text{ and } x_3)\) for the axial calibrations. The last column in Table II shows the location errors corrected for this bias.

The location precision obtained was sufficient for the purposes of this experiment, which was primarily to evaluate the balance structural geometry. As with the precision of the thrust resultant, a five-to-one improvement in this location precision would be readily achieved by reduction of strain gage creep and by the improvement in calibration technique that would normally result from more experience with the calibration of this type of balance.
An instrument designed in an orthogonal tripod geometry with short, rigid force-measuring links in a compact structure, can be used satisfactorily to measure the thrust vector (magnitude, direction, and location) produced by a rocket engine.

This type of vector thrust cell can also be conveniently calibrated with known axial and lateral loads in order to qualify the data obtained.
Figure 1. Scale Model Vector Thrust Load Cell
FIGURE 2. Force Link Arrangement of Model Cell
Axial Load ($F_z$)
Calibration Rod and Flexure

Side Load ($F_x$)
Weight Pan

Movable Sting

Figure 3. Installation on Calibration Rig
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Final Report - November 1969 to February 1970

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November 1970

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<table>
<thead>
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<th>KEY WORDS</th>
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<th>LINK B</th>
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