





U. S. ARMY ELECTRONICS COMMAND

Fort Monmouth, New Jersey



AD A099644

2.75 INCH ROCKET/AH-1G HELICOPTER WEAPONS SYSTEM BASELINE INSTRUMENTATION TEST REPORT

VOLUME II

AIRCRAFT INSTALLATION and TEST TECHNICAL AREA AVIONICS LABORATORY

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April 1972

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1.0 Data Format

The output data from the Data Acquisition Unit was recorded on a Leach Model 3200 digital magnetic tape recorder in a bit parallel pulse code modulated (PCM) format as shown in Figure 1.



For ease of presentation, the reproduced data is usually printed in a block format consisting of 120 words as shown in Figure 2. The words are written on the tape in a sequence that occurs by reading the data frame left to right, row by row. The data frame represents one complete sampling cycle by the Data Acquisition Unit (DAU). The DAU transmits the equivalent of 100 data frames per second to the recorder. Words S1 and S2, the synchronization words, are used to determine the frame structure. During the decommutation and formatting process, the computer searches the continuous data stream until the synchronization words are located. The computer then starts with the next data word and blocks the data into the desired 120 word format.

The Phase A and Phase B instrument configurations for the data presented in this volume are indicated in Figure 3 and Figure 4 respectively. The configuration charts list the assigned data words and engineering unit dimensions for each monitored parameter. The required measurements, necessary for performing the data analysis, are shown in Figure 5.

2.0 Recorded Data Conversion

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2.1 Sample Uctal Printout

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A typical octal data listing is shown on pages 6 through 15. The computer printout represents the data recorded as Run #138 on 24 August 1971. The recorded Phase B data extends for a period of 0.52 seconds immediately following the occurrence of event marker #1 which signals the aircraft approach to the rocket release point.

AI	A 2	A3	14	A 5	A 6	A7	81	CA	CD	BII	DI
A I	A 2	A 3	A 4	A 5	A 6	A7	B 2	CA	co	B12	02
Al	A2	A3	A4	A 5.	A 6	AT	83	CA	CD	813	D3
A I	75	A3	14	A 5	A 6	A7	84	CA	CD	814	D4
Al	AZ.	A 3	A4	A 5	A 6	A7	B5	CA	CD.	B 15	05
AI	A 2	A 3	A4	A 5	A 6	A7	86	CA	CD	816	CI
A I	A 2	A 3	A4	A5	A 6	A7	87	CA	co	817	C 2
A I	A 2	A 3	14	A 5	A 6	A7	88	CA	CD	818	CAL
A I	A2	A 3	A4	A5	A 6	A,7	89	CA	CD	ETI	ET2
A I	A?	A3	A 4	A 5	A 6	A7	B 10	CA	CD	\$I	S2

* * *

DATA	INPUT CHANNELS
WORD	INPUT
AI - A7	HIGH RATE ANALOG
8! - 83	SYNCHRO
84 - B18	LOW RATE ANALOG
DI	FLIGHT TEST RUN CODE
D 4	EVENT MARKERS

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DAU GERE	RATED INFORMATION
WORD	FUNCTION
ETI - ET 2	ELAPSED TIME CODE
CAL	CALIBRATION WORD
S1 - S2	SYNCHRONIZATION WOR

D

NOTE ALL OTHER WORDS ARE UNUSED.

FIG. 2 DAU DATA FRAME

PHASE	A	CONF	IGUR/	TION
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SENSOR	WORD	DIMENSION
IR Detector (Left)	Al	volts
Lateral Accelerometer	A2	ft/sec ²
Vertical Accelerometer	٨3	ft/sec ²
Fore/Aft Accelerometer	٨4	ft/sec ²
IR Detector (Right)	A5	volts
Roll Rate	A6	dearees/second
Yaw Rate	A7	degrees/second
Aircraft Pitch	BI	degrees
Aircraft Roll	B2	degrees
Aircraft Yaw	B 3	degrees
Pitch Rate	64	degrees/second
Angle of Attack* (#2LY)	B5	degrees
Angle of Attack (#2LP)	B6	dearces
Angle of Attack (#4RY)	E7	degrees
Angle of Attack (#4RP)	88	degrees
Angle of Attack (#3NY)	B13	dearees
Angle of Attack (#3NP)	B14	degrees
Angle of Attack (#1LY)	B15	degrees
Angle of Attack (#1LP)	B16	degrees
Angle of Attack (#5RY)	B17	degrees
Angle of Attack (#5RP)	B18	degrees

*Key for Angle of Attack Transmitter Position

L - Left	#1 Outboard
R - Right	#2 Inboard
II – Nose	#3 Nose
Y - Yaw	#4 Inboard
P - Pitch	#5 Outboard

FIG. 3

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PHASE B CONFIGURATION

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SENSER	WORD	DIMENSION
IR Detector (Left)	A1	volts
Lateral Accelerometer	.\2	ft/ s ec ²
Vertical Accelerometer	٨3	ft/sec ²
Fore/Aft Accelerometer	A4	ft/sec ²
IR Detector (Right)	۸5	volts
Roll Rate	A6	degrees/second
Yaw Ra te	A7	degrees/second
Aircraft Pitch	B1	degrees
Aircraft Roll	B2	degrees
Aircraft Yaw	B3	degrees
Pitch Rate	B4	degrees/second
LVUT* (LHF)	B5	inches
LVDT (LVF)	B6	inches
LVDT (LHA)	57	inches
LVUT (LVA)	B3	inches
LVDT (CHF)	B9	inches
LVUT (RVF)	610	inches
LVDT (REA)	611	inches
LVDT (RVA)	B12	inches
Angle of Attack (Nose-Yaw)	B13	degrees
Angle of Attack (Nose-Pitch)	B14	degrees
Angle of Attack (Left-Pitch)	B15	degrees
Angle of Attack (Left-Yaw	816	degrees
Angle of Attack (Right-Pitch)	B17	denrees
Angle of Attack (Right-Yaw)	B18	derrees

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*Key for Linear Variable Differential Transforms L-Left, N-Horizontal, F-Forward, R-Right, V-Vertical, A-Aft

FIG. 4



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2.2 Octal to Binary Data Conversion

The computer converts the 12 bit binary words, as recorded on the magnetic tape, into an octal representation during the decommutation and formatting process. It is often necessary to be able to reconstruct the binary word from the octal printout or to determine the octal data word from binary representation indicated on the data acquisition testset. The binary data word is represented by a parity bit, sign bit and ten data bits as indicated below:

Parity, Sign, Bit 10, Bit 9, Bit 8, ... Bit 1.

In order to convert the binary data to an octal form, the bits are divided into groups of three.

(Parity, Sign, Bit 10), (Bit 9, Bit 8, Bit 7),

The right most bit of each group is given a weight of 1. The center bit is given a weight of 2 and the left most bit of the group is given a weight of 4. The weights within each group are then added to give the octal representation. As an example the binary data word snown below will be converted into an equivalent octal word:

Binary Data Word: 111011100100

Grouped	(111)	(011)	(100)	(100)
Weighed	(4+2+1)	(0+2+1)	(4+0+0)	(4+0+0)
Octal Data Word	7	3	4	4

The reverse process is used to convert the data from octal to binary. An example is shown below:

Octal 4 1 0 7 $\begin{pmatrix} 1 \\ 4 \\ 2 \\ T \end{pmatrix} \begin{pmatrix} 1 \\ 4 \\ 2 \\ T \end{pmatrix} \begin{pmatrix} 1 \\ 4 \\ 2 \\ T \end{pmatrix} \begin{pmatrix} 1 \\ 4 \\ 2 \\ T \end{pmatrix} \begin{pmatrix} 1 \\ 4 \\ 2 \\ T \end{pmatrix} \begin{pmatrix} 1 \\ 4 \\ 2 \\ T \end{pmatrix} \begin{pmatrix} 1 \\ 4 \\ 2 \\ T \end{pmatrix}$

The weights of the bits are shown below the lines.

The resulting data bits are shown below.

 $(\underline{1} \underline{0} \underline{0}) \quad (\underline{0} \underline{0} \underline{1}) \quad (\underline{0} \underline{0} \underline{0}) \quad (\underline{1} \underline{1} \underline{1})$

and the binary word is 100001000111.

2.3 Binary to Analog Data Conversion

A binary data word is shown below:

Parity, Sign, Bit 10, Bit 9, Bit 8, ... Bit 1.

The data acquisition system converts the analog input into a digital representation with each bit representing 2^{N-1} counts with 3 being equal to the bit number. System sensitivity is set at 5 volts = 1000 counts. A one (1) in the sign bit position represents a negative analog sense. The following binary data word is reconverted back to the original input voltage as an example:

 Data Word
 0
 0
 1
 0
 0
 1
 1
 1
 0

 Bit Position
 P
 S10
 9
 8
 7
 6
 5
 4
 3
 2
 1

The total number of coupts becomes $(0 \times 2^{0}) + (1 \times 2^{1}) + (1 \times 2^{2}) + (1 \times 2^{3}) + (0 \times 2^{4}) + (1 \times 2^{5}) + (0 \times 2^{6}) + (0 \times 2^{7}) + (0 \times 2^{8}) + (1 \times 2^{9}) = 558 \text{ counts}$

The analog voltage represented by the binary word is equal to: 558 counts X 5 $\frac{mv}{count}$ = +2.790v

The data acquisition system uses an odd parity format. The parity bit becomes a 1 in order to make the number of bits in the word equal to an odd number. The parity bit therefore becomes a bit check on the data word. If the data word has no parity, yet has an even number of bits in the word then the word is in error and should be disregarded.

The sign bit represents the sign of the analog input to the data acquisition unit and may not be consistant with the desired coordinate system. Therefore, the sense of each transducer must be checked and sign conversion performed by the computer, if the sense is not proper.

2.4 Coordinate Determination

The coordinate system used in the analysis of the flight data is shown below.



Sensor	Sense	Direction
Yaw Gyro	+	CW (Negative Z Axis)
Pitch Gyro	+	Up (Positive X Axis)
Ro11	+	CCW (Negative Y Axis)
Yaw Rate Gyro	+	CW (Negative Z Axis)
Pitch Rate Gyro	+	Down (Megative X Axis)
Roll Rate Gyro	+	CCW (Negative Y Axis)
Fore/Aft Accelerometer	+	Fore (Positive Y Axis)
Vertical Accelerometer	+	Down (Negative Z Axis)
Lateral Accelerometer	+	Left (Negative X Axis)
Angle of Attack Transmitters	liaximum	CCW (*)
Linear Variable Differential Transformers (AC #67-15691)		
Left-Vertical-Forward	+	Up (Positive Z Axis)
Left-Vertical-Aft	+	Up (Positive Z Axis)
Right-Vertical-Forward	+	Down (Negative Z Axis)
Right-Vertical-Aft	+	Down (Negative Z Axis)
Right-Horizontal-Aft	+	Right (Positive X Axis)
Right-Horizontal-Forward	+	Right (Positive X Axis)
Left- Horizontal-Forward	+	Left (Negative X Axis)
 left-Hor ize ntal- A£t	+	left (Negative X Axis)

The sense of the transducer output voltage is shown below in Figure 6.

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*Axis alignment varies with configuration Note: Sense Readings taken at DAU Control Unit.

FIG. 6 SENSOR DATA SENSE

2.5 Transducer Scale Factors

The analog transducer scale factors are shown in Figure 7. The scale factors are used to determine the response of the sensor knowing the analog output.

Sensor Type	Scale Factor
Angle of Attack Transmitters	12.5 degrees/volts*
Linear Variable Differential Transformers	0.32 inch/volt
Accelerometer	1.25 G/volt
Rate Gyros	10 degrees/second/volt
Position Gyros	18 degrees/volt

*Average value for all transducers

FIG. 7 Transducer Scale Factors

2.6 Engineering Units Determination

A representative number of octal data words are converted into engineering units in Figure 8. The word number position can be seen in Figure 2 and the assigned parameter sensor can be determined from Figure 4.

The sample data frame being converted immediately follows the range time printout 236 0732 02.823 on the octal listing. The conversion of the octal word to a binary representation was performed as discussed in paragraph 2.2. The digital counts and analog outputs were determined using the technique discussed in paragraph 2.3. The scale factor for each of the applicable transducers was indicated in Figure 7. The resulting engineering units are shown in Figure 8 and compare with the data frame printout on page 49.

3.0 Engineering Units Printout

3.1 Phase A Data

ALL DESCRIPTION OF THE PARTY OF

The data presented on pages 22 through 47 is a segment of the data recorded for a Phase A flight test. The data, from Run #35 (recorded as octal 43), represents the data accumulated for a period of one second during the "straight and level" segment of the flight.

		. No IR nt	Re- Proper Chan- tion	Re- Proper Chan- tion	ibra- t/g	IR No	e Re- Proper	e Re- Proper		roper
	Remarks	Noise Level Trigger or Pulse Prese	Sign Change quired for Coordinates nel Calibra .8 volt/q	Sign Change quired for Coordinates nel Calibra .8 volt/g	Channel Cal tion .8 vol	Noise Level Trigger or Present	Sign Change quired for Coordinates	Sign Change quired for Coordinates		Sign Change quired for
Engineer-	ing Units	4036	-2.41 ft/sec ²	41.01 ft/sec ²	12.06 ft/sec ²	0100	2.9 deg/sec	1.2 deg/sec	-4.41 deg	+.180 deg
	Scale Factor	hone .	32.2ft/sec ² /volt .8	32.2ft/sec ² /volt .8	32.2ft/sec ² /volt	ltone	10°/sec/volt	10°/sec/volt	18°/volt	l3°/volt
Output @5mv/count	(volts)	.150	060	1.020	- 300	.040	.290	.120	245	.010
Digital	Counts	30	12	204	60	ω	58	24	49	2
ata Nord	Binary	011 110 000 COI	001 100 000 010	JOI 100 110 001	001 111 000 001	000 100 000 000	010 111 000 001	000 110 000 001	100 011 000 011	010 000 000 000
Ċ	Octal	4036	2014	4314	4074	0100	4072	4030	1909	0002
	Mord	۲.	A2	A3	A4	A5	йб	i,7	ßl	B2

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FIG. 8 OCTAL TO ENTINEERING UNITS CONVERSION

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Sign Change Re-quired for Proper Coordinates 2 volts g 0° 2 volts #0° Run #138 Remarks Engineer-ing Units +4.00 den sec +.180 deg -.075 in 4.60 deg -9.4 deg -.017 .038 .01 138 10 deg/sec/volt Scale Factor .32 in/volt .32 in/volt .32 in/volt .32 in/volt 12.5°/volt 12.5°/volt 18°/volt Output @5mv/count (volts) c10. 400 -.235 1.510 +.035 +.120 1.805 -.055 Digital Counts 80 138 \sim 302 47 361 = ~ 24 010 000 000 000 100 001 010 000 011 110 001 000 010 100 010 000 000 110 000 001 111 101 000 011 111 000 000 000 100 001 101 000 110 100 000 011 Binary **Data** Nord 4120 0003 0436 0212 6013 4030 6057 0551 0007 Octal brot Bl3 **B**]4 **B10 £**3 5 ເວີ 93 6 63

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FIC. 8 OCTAL TO ENVINEERING UNITS CONVERSION (CON'T)

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The analysis presented in paragraph 4.1 was performed on the data shown in the engineering units printout plus the data recorded in the succeeding two second period.

The data from the entire run is available on IBM compatible 9 track tape. Small representative samples were printed in engineering units in order to verify that the data was recorded, decommutated, converted and formatted properly.

3.2 Phase B Data

The engineering units printout shown on pages 49 through 62 is from a Phase B test flight flown on 24 August 1971. The sample of data shown represents the data collected for a period of approximately 1/2 second.

The fourth engineering units data frame on page 49 is the sample data frame converted from the octal data as described in paragraph 2.6.

The data used for the analysis, performed in paragraph 4.2 and 4.3, on the LVDTs and accelerometers was part of a "straight and level" flight from Run 138.

4.0 Subsystem Validation

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The following paragraphs present an analysis of retrieved data samples employing various statistical techniques for the purpose of verifying the performance of the airborne instrumentation.

Statistical operations were performed to obtain the data averages, RHS values, frequency spectrum profiles (Fourier analysis) and correlation between sensor data for the angle of attack transmitters, linear variable differential transformers and the inertial reference system accelerometers. The relative tracking of the above mentioned sensors is illustrated in X-Y plots of the retrieved data.

Analysis was performed on the trigger and IR detector data to determine the firing delay characteristics of the rocket system and the average velocity of the 2.75" Rockets.

All statistical calculations were performed on an IBM 360 computer.

4.1 Angle of Attack Transmitter Analysis

A sample of the data used for the analysis of the angle of attack transmitters (AAT) for Run 35 is shown on pages 22 through 47. The data upon which the analysis was performed was recorded during a Phase Λ Configuration 2 flight on June 23, 1971. The sample was retrieved during a one second period. The analysis was performed upon this data and the data in the succeeding two second interval.

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The angle of attack data was corrected prior to the analysis for the mounting alignment of the AAT pods. The engineering units listing is in an uncorrected form.

4.1.1 Data Statistics

Results of the angle of attack statistical analyses are shown in Figures 9 and 10.

Due to the physical mounting of the angle of attack transmitters, correction factors have been applied to the data in order to compensate for the mounting offsets. The nose pod was pitched upward by 8 mils and was angled to the right by 7.5 mils. These offsets were converted to correction factors of 0.450 degrees for the nose pitch and 0.421 degrees for the nose yaw. The correction factor for the nose pitch was subtracted from the data and the correction factor for the nose yaw sensor was added to the sensor data prior to the analysis. The four launcher pods were all pitched upward by 80 mils. This offset, equivalent to 4.499 degrees, was subtracted from the pitch angle of attack readings.

The mean values for each of the pitch angle of attack transmitters and the pitch gyro are shown in Figure 9. These values indicate the average reading for the sensors over the period of the sample.

The root-mean-square (RMS) values for each of the parameters were calculated to indicate the degree of excursion of the data. The RMS values for the sensors fell in a range within 0.1 of the absolute value of the mean values. This indicates that most of the data samples fell within a very narrow range of mean value.

The standard deviation was calculated in order to provide a measure of the data dispersion. For a normal distribution, the standard deviation or $\pm \sigma$ indicates the range in which 68.2% of the samples were located about the mean. For the angle of attack Sensor in the Pitch #1 position, 68.2% of the samples were within ±.9150° of the mean value (-5.7427°).

A two sigma value (2σ) , or twice the value of the standard deviation, indicates the data band in which 95.5% of the samples fell. A 3 σ value indicates the data band in which 99.7% of the values were located. For the above example, this would indicate that 95.5% of the value are within $\pm 1.830^{\circ}$ of the mean and 99.7% are within $\pm 2.745^{\circ}$ of the mean. It will be shown later in the Fourier Analysis Section that the predominant portion of the data excursion is cyclic and in fact these deviation measurements are accurate vibratory motion induced sensor readings.

The variance, which is equal to the square of the standard deviation, is a measure of the range of the data and presented in Figure 9.

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Similar data analysis is presented for the yaw angle of attack transmitters and the yaw gyro which is shown in Figure 10.

4.1.2 Data Correlation

A computer program was written to assess the degree of correlation between data signals and calculate correlation coefficients to measure data confidence level. The results of the analysis are shown in Figures 9 and 10 for the pitch and yaw sensors, respectively. The correlation between the pitch angle of attacks was very good with a .8631 coefficient between Pitch #1 and Pitch #3 being the lowest. Pitch #3 was located on the nose of the aircraft and sensed the airflow approximately 0.12 seconds earlier then the launcher sensors. This would be a contributing factor to the lower correlation factor.

The lowest correlation factor between the pitch sensors #1, 2, 4, 5 was 0.9415 and the highest factor was 0.9864. The high correlation between these sensors indicates that the angle of attack transmitters were responding to the airflow and the relative tracking movements of the individual sensors were in near perfect agreement.

The correlation between the gyro pitch and the angle of attacks was very poor. This indicates that the helicopter flight profile was not effected by the cyclic change in airflow pattern. Reviewing the engineering units printout shows that the pilot was able to maintain his pitch attitude even though abrupt changes in the airflow occurred.

Identical information is available for the yaw angle of attack in Figure 10. From the mean values it can be seen that the airflow around the aircraft was almost symmetrical and indicates a streamlining effect with relative wind flowing down and outboard of the fuselage.

4.1.3 Frequency Spectrum Determination

A standard computer subroutine was used to analyze the frequency content of the various recordings. This operation calculates the Fourier coefficients over one cycle. Based on previous observations, the fundamental frequency of these signals is 11 Mertz (period equals .09 seconds) and corresponds to the natural helicopter rotor frequency. Since the data acquisition system records at a rate of 100 samples per second, then 9 data points are necessary for a calculation. For each parameter, separate calculations were made for consecutive blocks of nine data points. The results of these calculations are shown on pages 67 through 74.

The accuracy of each DC component can be verified by checking the 9 appropriate data points. Since the AC variations of these signals are quite low, then the Fourier coefficients are correspondingly low. It can be noticed in the pitch calculations for data points 181 to 189, there was a significant increase in the magnitude of the coefficients. Referring to the plot of the pitch signals in Figure 11, it is seen
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that there was a pronounced change in amplitude at 1.8 seconds. Since this appears as a ramp signal in the calculation, the Fourier analysis should and did produce a relatively high value for the fundamental and all its harmonics. Due to the number of data points available in one cycle of the signal, calculation of any harmonics above the 4th would be meaningless.

It should also be noted that the gyro pitch (Pitch 6) harmonic coefficient was at or near zero for every calculation. To confirm this result, refer to Figure 11 and observe that there was virtually no variation in this signal.

4.1.4 Relative Data Tracking

The developed computer program that was written to perform that analysis on the various sensors also produced a punched card file of the data points under consideration. These cards were run on a digital plotting system for viewing of the data. The results of the gyro pitch and pitch angle of attacks are shown in Figure 11.

The plots show exactly what was indicated by reviewing the data in paragraphs 4.1.1 through 4.1.3. Examining the plots, it can be seen that the aircraft was at a very steady pitch down angle which tends to verify a standard deviation of .071. The consistent relative tracking of the sensor dictates the existance of the high correlation coefficient previously calculated. It can be seen that the nose angle of attack sensors led the others by about 0.12 seconds. This was due to the nose sensor being located 13 feet alread of the launcher sensors. The abrupt change in the airflow at approximately 1.8 seconds would justify the high frequency coefficients calculated during that period.

The yaw gyro and the yaw angle of attack plots are shown in Figures 12 and 13. A review of the plots shows that the analysis presented in Figure 10 is realistic.

The plots of the Angle of Attack Transmitters were accomplished with corrected data to adjust for the pod offsets as discussed in paragraph 4.1.1.

4.2 Linear Variable Differential Transformer Analysis

A segment (500 milliseconds) of the raw octal data used in the analysis of the LVDTs is presented on pages 5 through 15. The data, from Run 138, was retrieved on 24 August 1971 on aircraft #67-15691 in a Phase B configuration. The analysis was performed on data accumulated in a three second period immediately following the occurrence of Event Marker #1 (0001 in word D4). The engineering units data listing shows the data frames for the first 0.500 seconds of the three second period (Pn 40-52).

4.2.1 Data Statistics

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The analysis of the horizontal and vertical LVDT data is shown in Figures 14 and 15 respectively.





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The low mean data values indicate that the sensors were accurately nulled prior to the test flight and remained nulled throughout the sampled time.

From the standard deviation it can be determined that 95.5% of the samples for the left/horizontal/forward LVDT are within $\pm .0638$ inches of the mean. Therefore it can be stated during the sampled period, a straight and level flight, the left forward position of the rocket launcher was moving approximately 0.12 inches in the horizontal plane.

4.2.2 Data Correlation

The correlation, as shown in Figure 14, between the horizontal LVDT sensors indicates that the movement in the yaw plane was mainly a rotational motion. The left fore and aft LVDTs have a correlation factor of -.9542 indicating that the front and back of the launchers were moving simultaneously in opposite directions. The motion of the left and right launcher correlates quite well with the forward LVDTs, having a correlation coefficient of +.6354 and the aft LVDTs, having a coefficient of .9165.

The correlation coefficients for the vertical LVDTs are shown in Figure 15. The coefficients between the fore and aft sensors were negative defining a pitching motion as expected. The coefficients were -.3 and -.4 for the right and left sides respectively and the low correlation figure indicates a combination of translation as well as pitch motion in the vertical plane. The launcher is supported at multiple points and therefore the vertical movement is not a simply described motion.

4.2.3 Frequency Spectrum Analysis

Calculations of the Fourier coefficients for the LVDTs were performed on the sensor data. The resultant coefficients are tabulated on pages 82 through 85.

The data indicates that there was significant harmonic content in the sampled data. To determine the significance of the harmonics of the 11 Hertz fundamental, the data could be normalized by dividing each of the coefficients by the DC values or the coefficient of the fundamental. For the LVDT #2 (left/vertical/forward), the coefficients for the multiples were large compared to the coefficients of the other data and in relation to its fundamental and DC values. This would indicate several significant harmonics were present in the data.

The coefficients for LVDT #5 (right/horizontal/forward) are approximately 100 times smaller, which can be misleading unless they are compared with the DC and 11 Hz coefficients. The results indicate that the harmonic content was as great as that of LVDT #2.

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4.2.4 Relative Data Tracking

Profiles of the vertical and horizontal LVDTs are shown in the data plots, Figures 16 through 23. The 11 Hz fundamental frequency is apparent in all figures.

Examining Figures 13 and 20, it is apparent that the harmonic content was considerable for the LVDTs as was discussed in paragraph 4.2.3.

The degree of movement of the launchers can be determined by calculating the magnitude of the peak values from the plots.

The curve connecting the positive peaks of the LVDT (LVA) data plotted in Figure 21 and the negative peaks of the LVDT (LVF) data plotted in Figure 20 were parallel consistantly over the interval of time shown. This parallel envelope movement indicates that translational motion of the launcher occurred during the normal flight. The plot indicates that the launcher translated approximately .014" (See Figure 24).

The peaks described within the envelope indicate that the front of the launcher peaked in one direction, while the rear of the launcher peaked in the opposite direction. This indicates a significant amount of rotational motion. From the curves it was determined that the launcher oscillated within approximately a 1 mil excursion. The combination of the translational and rotational motion caused a complex launcher motion that would result in low correlation coefficient for the LVDTs.

The rotational velocity of the launcher pod can be calculated from the slope of the LVDT curve. The calculation for the left launcher indicates the launcher rotates at a rate of approximately 100 mils/second.

4.3 Accelerometer Analysis

The data used for the analysis of the accelerometers is shown in the data frame of the engineering units printout, pages 49 through 55. The flight data was described in paragraph 4.2. The accelerometers are sampled 10 times per frame/1000 times per second and the analysis was performed on the first 260 data points. This data was retrieved in 0.260 seconds, all of which is presented in the first 26 data frames of engineering units printout.

4.3.1 Data Statistics

The accelerometer data analysis is presented in Figure 25.

It can be seen from the data that the mean values for the lateral and fore/aft accelerometers were -0.2336 and +2.9330 ft/sec² respectively, indicating a lack: of predominant acceleration in the left, right, fore or aft direction. This was consistant with the known straight and level flight profile. The high RMS and standard deviation indicates that the











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aircraft was experiencing considerable acceleration in all directions (about 1/3g) but was cyclic as shown by the fow mean value.

The RHS value for the vertical accelerometer (ACCUD) was 32.4141 ft/sec², consistant with the normal gravity vector.

4.3.2 Frequency Spectrum Analysis

The Fourier coefficients for the accelerometer data are shown on pages 98 through 103.

It can be seen that the harmonic content of the data is significant up to approximately 55-Hz.

4.3.3 Relative Data Tracking

The relative data tracking of the accelerometer data is shown in Figures 26, 27, and 28. The accelerometer data was sampled on a DAU high rate channel (1000 samples/second) and therefore many more points per cycle were available for analysis. Only the first 260 data points (0.26 seconds) were plotted.

It can be seen from the plots that the acceleration was cyclic and did wary over a considerable range.

4.4 Trigger and IR Detector Analysis

The data for the analysis of the trigger and IR detector analyses is presented on pages 107 thru 116. The data was retrieved during the Phase B flight on 24 August 1971, previously described in paragraph 4.2.

The trigger pulse was indicated on channels A1 and A5 by a pulse of approximately 1.5 volts with a duration of approximately 1.5 ms. The rear IR detector produced a -1.5 volt pulse when the IR in the plume of the rocket was detected. The forward IRs produced a -0.5 volt pulse when the IR was sensed.

To determine the delay characteristics of the rocket system and the average velocity of the launched rocket, the Al and A5 channels were monitored for the pulse and the times of occurrence noted. The Al channel monitored the left detectors and the A5 channel monitored the right side detectors.

4.4.1 System Delay Characteristics

The octal reading for channels Λ 1 and A5 of 4036 and 4011 respectively represent the ambient analog noise level on the channels. The channels were monitored for the trigger pulse represented by a significantly larger voltage level.

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The trigger was detected in the data frame, time 11.6310, on channel A1.

In the data frame time, 11.9010, the IR detector sensed the rocket plume indicating that a rocket had cleared the right launcher. In the following frame, it is indicated that a rocket had cleared the left launcher.

To determine the rocket egress delay characteristic the time difference between the trigger and the first IR pulse was obtained.

DELAY = IR#1 - TRIGGER

DELAY (right side) = 11.907 seconds - 11.631 seconds

.276 seconds

DELAY (left side) = 11.916 seconds - 11.631 seconds

= .285 seconds

This delay time was found to be typical of most firing runs.

4.4.2 Rocket Velocity Determination

The forward IR was located 60 ± 1 inches forward of the rear detector. Therefore the average velocity can be obtained by determining the time taken to traverse the distance.

The occurrence of the 2nd IR pulse was indicated in data frame time 11.951.

The average velocity of the rocket fired from the left launcher is determined below.

VELOCITY
=
$$\frac{5 \text{ ft}}{\text{Time (IR #2)} - \text{Time (IR #1)}}$$

= $\frac{5}{11.956 - 11.916}$
= $\frac{5}{.040}$ = 125 ft/sec

The average velocity of the rocket fired from the right launcher is determined below.

VELOCITY =
$$\frac{5 \text{ ft}}{11.954 - 11.907}$$

= $\frac{5}{.047}$ = 107 ft/sec

These values were found to be typical of most firing runs.

