



(72)

,	87048,	,	501
,	87110,	,	5312
,	87109,	,	7405
,	87124,	,	2872
,	55313,	,50	3421

(74)

:

---

(54)

---

,	(S) 가	(33n)	,	(S)	(35)	(S)	,	(S)
,		(11 <sub>1</sub> ,11n)	,	.		(S)		

1

,

가 ( misalignment), (tu rbogenerator) 가

( 가 0.01 ( 10 (mile)) ,RPM 가

ogies) (eddy - current) (Lucent Technol

(non - obtrusive) ( 150 (mils) 500 (mils) 9000 (9000 RPM) 10 (mils) 9000 RPM

(Crusader for the Army), (the Advanced Amphibious Attack Vehicle for the Marines), (Joint Strike Figh ter, JSF) 가

( )

)

(

가

1

2

3

4a

가

가

4b

4a

5

가

6

5

가

7

5

가

1 (21) (S) (S) (11n) (51) 11<sub>1</sub> - 11<sub>n</sub>; (31) (33n); (41); (31) (bus, 43) (35) 가

1 (21) (11n) (S) (11n) (31) (21) (S) (11<sub>1</sub>, 11<sub>2</sub>, 11<sub>n</sub>) 1 (11<sub>1</sub> - 11<sub>n</sub>) 0.15 0.4 (31) (35) (11<sub>1</sub> - 11<sub>n</sub>) (bundle) (31) (3) 5) - (35) (51) (33n) (41)

( ) (33n) (11<sub>1</sub> - 11<sub>n</sub>) 가 (11<sub>1</sub> - 11<sub>n</sub>) (35) 가 (35) ( ) (11<sub>n</sub>) (11<sub>1</sub>) (S) 가

( ) 2 2 100 (mils) 가 (51)

3 3 가 가 ( )

(35) (33n) (31) (35) ,  
(35) (35) , (S)  
(33n) (35) 120  
(33n) (11n)  
(33n) (C) , (  
) 4a (37  
1 - 37<sub>n</sub>) (11n)  
가 ( 6 )가 (solution) 가 1  
3 (37<sub>1</sub> - 37<sub>3</sub>) , 4 (37<sub>4</sub>) (31)  
, 5 (37<sub>5</sub>) (31)  
1 2 ) ( , , , ,  
) ( (35) (37n)  
1) ) ( ) ( (4  
11n) (11n) (33n) (

(11n) (41)  
(51) (51) (43)( (S) 10 450 (mils) 0.1 2.5  
(51) (S) 가 9000 RPM  
5 (11n) , (51) RPM 가 (61),  
가 (63n), 가 (65)  
(11n) (31)가 (31) (33  
n) ( ) (33n) ( ) ( ) ( )  
) 가 ( )  
(11n) , (11n) (33n) (33<sub>1</sub>)  
33<sub>2</sub>, 33<sub>3</sub> 33n RPM 가 (61)  
(33n) (37n) 가 (63n)  
(11n)

6 , 가 (63n) (11n)  
(33n) (371 - 375)

가 (33n) 가 (63n) 가 (51) ( , ) , .

6 (11n) 가 (63n) (37n) ( ) , 가 , .

가 (65) 가 (63n) (Kaman) 가 (31) 가 가

(Mathmatica) (MatLab) (ASICS) (S) (33n) 1 (mapping)

가 (33n) (51) (S) (S) (51) 가

가

가

(57)

1.

,

,

,

가 ;

;

(bus) ;

가 ; ,

,

,

2.

1 , 0.15 0.4 (inch)

3.

2 ,

4.

3 , , ,

5.

4 ,

6.

5 ,

7.

6 , 가

8.

7 , 가 , RPM 가 ,  
 가 ,  
 RPM 가 ,  
 가 ,  
 가 ,  
 가 .

9.

8 , 1 , 2 , 3 , 4 5 가 , 4 ,  
 1 , 2 , 3 , 5

10.

9 , , , , , .

11.

10 , 1 2 .

12.

;  
 ;  
 ;  
 (bus) ;  
 가 ; ,

13.

12 ,

14.

13 ,

0.15 0.4 (inch)

15.

14 ,

16.

15 ,

17.

16 ,

18.

17 ,

가

19.

18 ,

가 ,

가

RPM 가 ,

RPM 가

가

가

20.

19  
1 , 2 , 3 , 4 , 5 가 , 4 , 5 ,  
가

21.

20 , , , , .

22.

21 , 1 2 .

23.

, ; ; ;  
(bus) , ; ;  
가 ;

24.

23 , 0.15 0.4 (inch)

25.

24 , .

26.

25

,

,

가

,

27.

,

,

;

,

;

;

(bus)

,

,

,

가

;

,

가

,

.

28.

25

,

0.15

0.4

(inch)

,

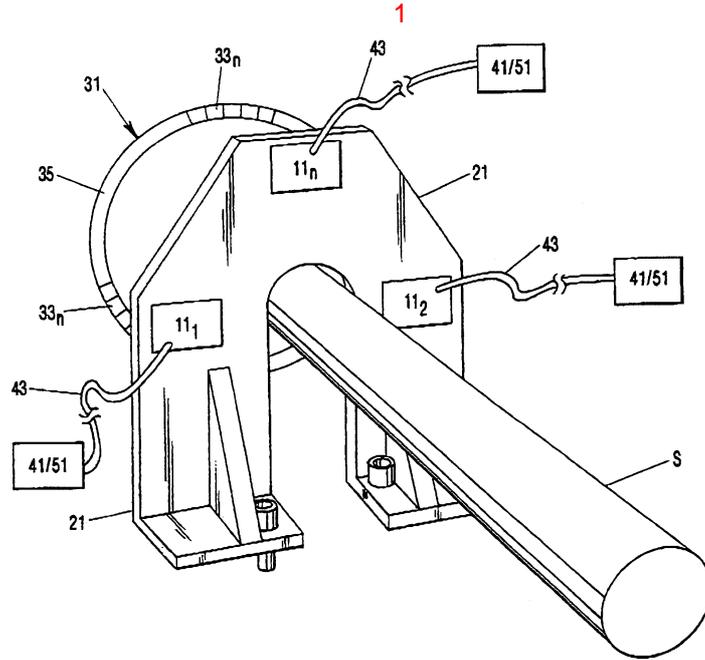
29.

26

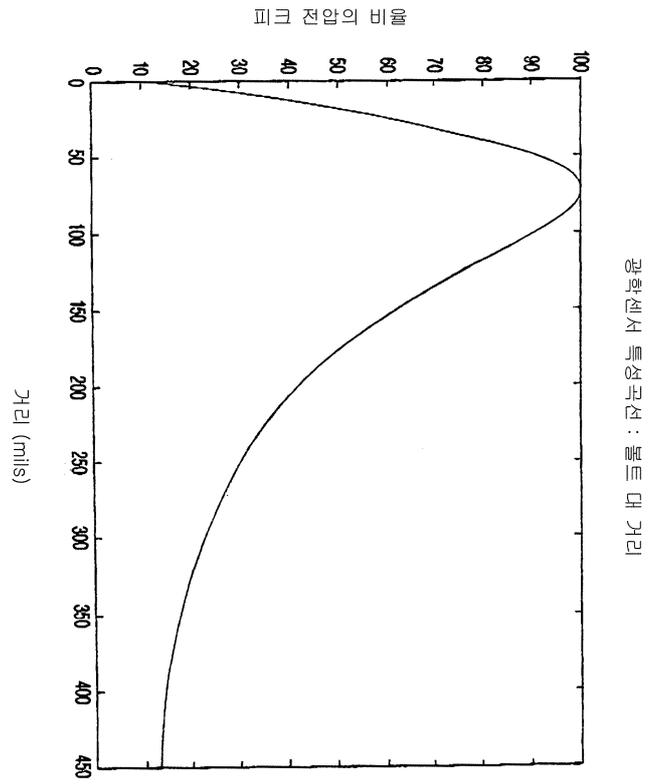
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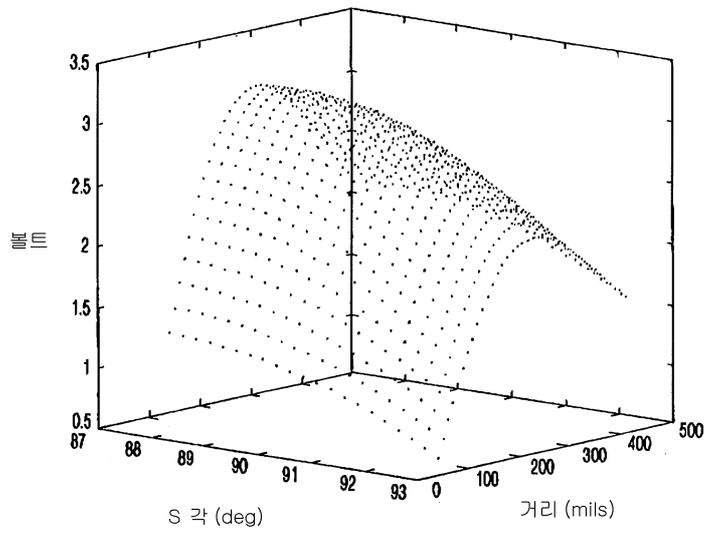


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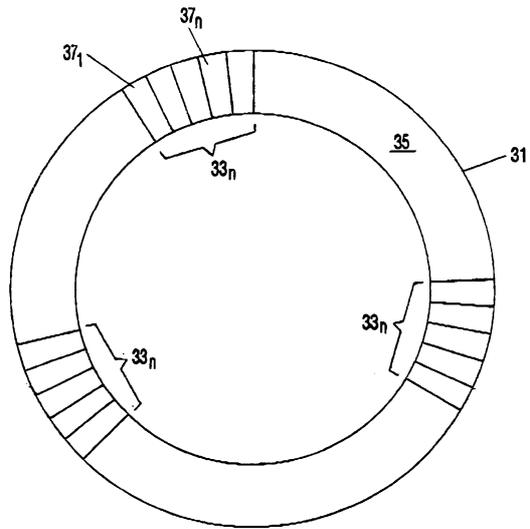
3

Y=90도에서 센서 전압

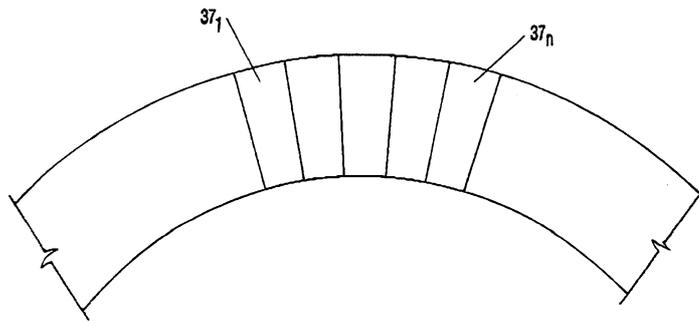


4

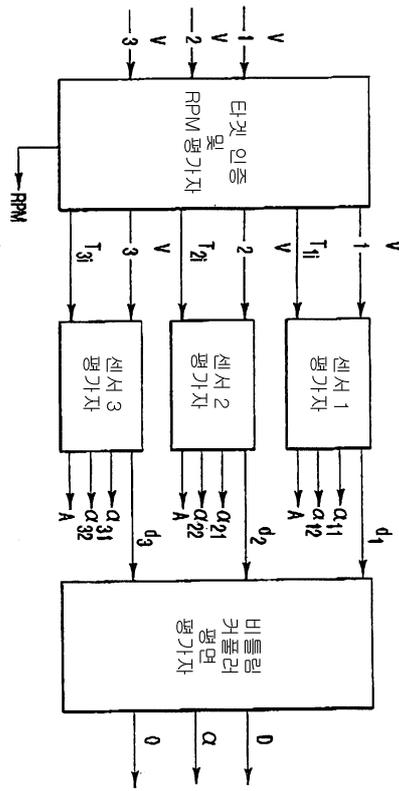
(a)



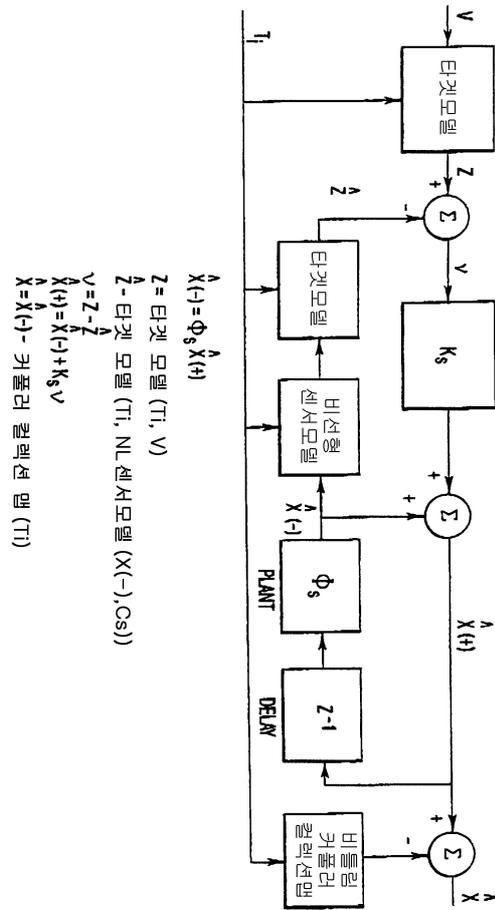
(b)



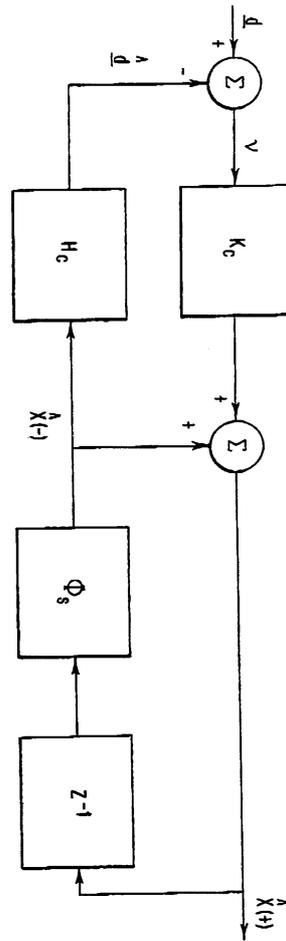
5



6



7



$$\begin{aligned} \hat{X}(-) &= \Phi_s \hat{X}(+) \\ \hat{A} &= H_c \hat{X}(-) \\ \nu &= \hat{d} - \frac{\hat{A}}{\hat{d}} \\ \hat{X}(+) &= \hat{X}(-) + K_c \nu \end{aligned}$$