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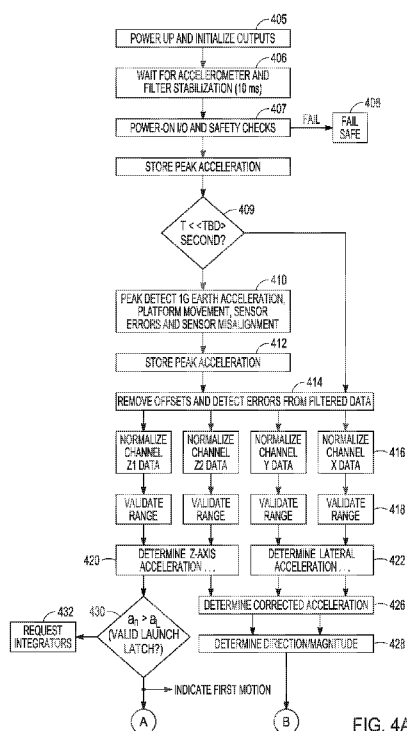


FIG. 4A

(57) Abstract: A motion analysis system includes an acceleration measuring device, an acceleration processor, a velocity processor, a distance processor, a peak velocity processor, a profile correlation processor, and a vehicle action processor. The system determines a time for an initiation of an action for a vehicle by determining that a distance traveled by the vehicle is greater than a safe separation distance and that a peak velocity is greater than a minimum velocity. The system initiates the action for the vehicle based on the verified position of the vehicle and the confirmed profile data as determined by the profile correlation processor, and based on the determination that the distance traveled by the vehicle is greater than the safe separation distance and that the peak velocity is greater than the minimum velocity as determined by the vehicle action processor.

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MOTION ANALYSIS UNIT

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CLAIM OF PRIORITY

[0001] This patent application claims the benefit of priority to U.S. Application Serial No. 15/331,157, filed October 21, 2016, which is incorporated by reference herein in its entirety.

10

GOVERNMENT RIGHTS

[0002] This invention was made with United States Government support under Contract number N00024-13-C-5403 with the Department of the Navy. The United States Government has certain rights in this invention.

15

TECHNICAL FIELD

[0002] The present disclosure relates to a motion analysis unit.

BACKGROUND

[0003] As requirements for missile technology evolve, there is a growing need for enhanced sensing of rocket motor performance. Precise confirmation of flight profile data is needed in order to accurately and independently determine distances and velocities attained as well as time in flight to precisely determine if and when events such as a stage separation, a missile destruct, or a warhead function are executed. In addition, safety certification authorities recommend eliminating distributed safety systems (which currently require additional devices, cabling, and connectors) in new or updated weapons.

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Brief Description of the Drawings

[0004] FIG. 1 is a block diagram of a rocket motor ignition system.

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[0005] FIG. 2 is a block diagram of a motion analysis unit.

[0006] FIG. 3 is a diagram of an acceleration profile.

[0007] FIGS. 4A and 4B are a block diagram of a system and process to analyze motion of a vehicle.

Detailed Description

5 [0008] In the following description, for purposes of explanation, numerous specific details are set forth in order to provide a thorough understanding of the various aspects of different embodiments of the present invention. It will be evident, however, to one skilled in the art that the present invention may be practiced without all of the specific details and/or with
10 variations, permutations, and combinations of the various features and elements described herein.

[0009] An embodiment provides an accurate environment detection method for rocket motor performance, and the detection of first motion, safe separation distance having been reached, and rocket motor cut-off deceleration.
15 The embodiment includes multiple independent circuits that are used to enable an integrated safety feature, an enable circuit, a measurement circuit that contains a distance measurement circuit, and a profile measurement circuit with an electronic timer and first motion detect. A distance measurement subsystem is used to determine when the vehicle, rocket, or other weapon has achieved a
20 safe separation distance. Algorithms are implemented in an anti-fuse field programmable gate array (FPGA), which receives sampled data from an analog accelerometer. An embodiment detects the initial launch acceleration and will latch when the rocket motor starts to burn out or reduce acceleration. The sensor outputs are monitored in an autonomous validation circuit for proper operation
25 and error detection. If the data are in error, the entire device will go into a fail-safe state. The device will signal detected events including but not limited to weapon first motion, motor profile verification, safe separation distance detection, and rocket motor burnout.

[0010] An embodiment integrates several subsystems into a single unit,
30 providing signals for key events, and eliminating the need for separate circuit interrupters. Specifically, outputs from several acceleration channels are combined in a unique manner. Two longitudinal axes (z axes) are in the line of flight of the weapon or vehicle. A low frequency z axis accelerometer/senor

encompasses the expected range of accelerations and a high frequency z axis accelerometer/sensor covers any anomalies, such as an ejection. The low frequency z axis accelerometer/sensor is kept close to expected values to maintain accuracy (the two z axis channels should correlate and provide
5 accuracy). Lateral accelerometers/sensors x and y are used to detect errors. To determine velocity and distance from the acceleration data, bit shifts instead of division operations are executed to implement a rectangular integration.

[0011] An embodiment is a new measurement system that is more accurate than previous devices. Redundancy in power, resets, and clocks
10 dynamically compensates for launch angle, ship roll, and environment movement prior to measurement start, among other things. The system accurately determines first motion (threshold programmable), and determines a programmed distance (also programmable) while verifying a proper thrust profile. The system also includes motor profile verification for performance.

15 [0012] In particular, an embodiment includes methods, systems, and computer program products for analyzing the motion of a vehicle, for example a missile or rocket, and determining what actions to take and when to take such actions based on that analysis. The methods, systems, and computer program products first detect an initial motion of a vehicle using data received from four
20 accelerometers (two longitudinal accelerometers and two lateral accelerometers). The initial motion serves as a baseline. The methods, systems, and computer program products calculate a velocity of the vehicle by adding to a previously-computed velocity an average of a current acceleration and a previously-measured acceleration, and then calculate a distance traveled by the vehicle by
25 adding to a previously-computed distance an average of a current velocity and a previously-computed velocity. Thereafter, the methods, systems, and computer program products determine a peak velocity of the vehicle, verify a position of the vehicle using a motion profile database, and confirm data in the motion profile database. Here, the methods, systems, and computer program products
30 are looking for the vehicle to be at certain places at certain times. The methods, systems, and computer program products then determine a time for an initiation of an action for the vehicle by determining that the distance traveled by the vehicle is greater than a safe separation distance and that the peak velocity is greater than a minimum velocity threshold. Finally, the methods, systems, and

computer program products initiate the action for the vehicle based on the verified position of the vehicle, the confirmed profile data, the determination that the distance traveled by the vehicle is greater than the safe separation distance, and the determination that the peak velocity is greater than the minimum
5 velocity. Further details of these methods, systems, and computer program products are discussed herein.

[0013] The methods, systems, and computer program products increase the accuracy of an initiation of a vehicular action by approximately 20% of the measured distance and/or velocity to less than 2% of the measured distance
10 and/or velocity. In order to meet requirements to activate, system margins are decreasing and need to be measured with precision previously not possible. The device needs to be precise enough to identify or discriminate features in the motor burn but sense the acceleration profile. The methods, systems, and computer program products also compensate for launch angle and periodic
15 motion, among other things. In this compensation, the methods, systems, and computer program products determine environment movement (*e.g.*, of a launch platform) prior to the start of (acceleration) measurements. The methods, systems, and computer program products further determine in real time key parameters related to motion and verify a motion profile.

20 [0014] Additionally, the methods, systems, and computer program products sense acceleration of complex profiles in order to make vehicular launch and/or ejection decisions and validate rocket motor performance through correlation with an expected profile. The methods, systems, and computer program products are implemented via multiple independent circuits, which
25 enable a safety subsystem. Sensor (accelerometer) outputs are monitored in an autonomous validation circuit to verify proper orientation of a vehicle and to detect errors. If errors are detected, the methods, systems, and computer program products go into fail-safe mode. The methods, systems, and computer program products signal detected events such as first motion of a vehicle, a
30 verification of a motor/motion profile, a safe separation distance, and a burnout of a vehicle motor. The methods, systems, and computer program products integrate several subsystems into a single unit and provide signals for key events, thereby eliminating a need for separate circuit interrupters.

- [0015] **FIG. 1** illustrates a vehicle or rocket motor ignition system **100**. The system **100** includes both a safety device and parts of a weapon system that contribute to vehicle/rocket firing. Specifically, the system **100** includes a launch platform **110** and the weapon system **120**. The launch platform **110** provides an enable command **115** to an ignition safety device **130**, and the weapon system **120** provides a fire command **125** to the ignition safety device **130**. Upon reception of the fire command **125** by the ignition safety device **130**, a fire signal **135** is transmitted to the motor **140**, resulting in firing of the motor and the initiation of the vehicular/rocket action.
- 10 [0016] **FIG. 2** is a block diagram of a motion analysis system **200**. In general, it depicts a representative system that will use a motion analysis unit. It is incorporated as one element in a classic ignition safety ignition design. Block **220** shows an independent logic element that is a coarse measurement required by safety certification authorities and is used to add safety to prevent false triggering from the precision measurement circuit. The motion analysis system **200** includes a motion analysis unit **230**. The motion analysis unit **230** includes motion or acceleration sensors **231**. The acceleration sensors **231** include two z-axis or longitudinal sensors **232A** and **232B**, a first lateral or x-axis sensor **233**, and a second lateral or y-axis sensor **234**. The **232A** longitudinal sensor is a low sensor, and the **232B** sensor is a high sensor. As noted above, the low sensor **232A** encompasses the expected range of accelerations and the high sensor **232B** covers any anomalies, such as an ejection. The output of each acceleration sensor is fed into a low pass filter **235**. The output of the filter **235** is fed into a sampler that is used to convert an analog voltage from the filter into a digital word that is processed by the algorithms implemented in the FPGA sensor **236**. The output of the sensor **236** is received by a receiver **237**, which provides input to a profile correlation module **238**, which further receives parameters from a motion profile database **238A**. As explained further herein, the profile correlation module **238** will search acceleration data for key features that will validate that the acceleration for the particular application. The motion analysis unit **230** further includes a module **239** that includes POST circuits, reset and clocking circuitry, and provides diagnostic output.
- 25 [0017] **FIGS. 4A – 4B** are a block diagram illustrating an example method and system of analyzing a motion of a vehicle. **FIGS. 4A – 4B** include a

number of process blocks **405 – 490**. Though arranged somewhat serially in the example of **FIGS. 4A – 4B**, other examples may reorder the blocks, omit one or more blocks, and/or execute two or more blocks in parallel using multiple processors or a single processor organized as two or more virtual machines or sub-processors. Moreover, still other examples can implement the blocks as one or more specific interconnected hardware or integrated circuit modules with related control and data signals communicated between and through the modules. Thus, any process flow is applicable to software, firmware, hardware, and hybrid implementations.

10 **[0018]** Referring now to **FIGS. 4A** and **4B**, in an embodiment, a motion analysis system for a vehicle and/or rocket, wherein the motion analysis system includes a first longitudinal accelerometer, a second longitudinal accelerometer, a first lateral accelerometer, a second lateral accelerometer, and a computer processor, executes a plurality of the following operations. At **405**, the system is
15 powered up and outputs are initialized. Acceleration sensor outputs are unpredictable at power on and need to be verified by the measurement system before they are used. A delay is inserted to allow them to stabilize and then the initial measurements are verified to an expected range at initialization before they are used for measurements. If the acceleration sensor does not respond
20 according to expectations, the entire subsystem will enter the failsafe mode. At **406**, the system executes a delay until the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, the second lateral accelerometer, and a filter stabilize. In an embodiment, at **407A**, the filter is a 500 Hz low pass filter that is selected to minimize the internal clock rate and
25 energy consumption, but to sample fast enough to capture key features in the profile. At **407**, the system is powered on and safety checks are executed. Such safety checks can include verifying that the power on and reset have initialized critical registers, that system clocks have been checked and verified, and that intelligible data have been received from the accelerometers. If any problems
30 are detected, the system enters a fail-safe mode at **408**.

[0019] At **409**, the system delays for a predetermined amount of time, for example 30 seconds. The delay required is to balance between the characteristic movement of the platform and the time allowed in the mission timeline to determine any effects of any detected errors. At **410**, the system independently

minimizes errors associated with a channel associated with each of the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, and the second lateral accelerometer. The system minimizes these errors by detecting and removing fixed offsets. For example, the system detects the acceleration of the earth, launch platform movement, sensor errors, and sensor misalignment. Regarding the sensor misalignment, the longitudinal and lateral accelerometers should be orthogonal to each other, and the two lateral accelerometers should be orthogonal to the longitudinal accelerometer. At **412**, a peak acceleration is stored. The peak acceleration is measured by sensing a rise in the acceleration consistent with the expected profile and a series of samples of decreasing values. The maximum measured value is stored until it is replaced by a higher peak value. At **414**, any detected offsets and errors are removed from the filtered data (**407A**). Operations **409** through **414** can be referred to as channel compensation operations.

[0020] At **416**, the system normalizes data received from the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, and the second lateral accelerometer. The normalization is executed in order to account for the differences in the different individual accelerometers, which could include differences resulting from the use of different accelerometers from different manufacturers. The data from the accelerometers are independently scaled so that the resolution of the data matches and the data can be combined to create a corrected acceleration. At **418**, the system verifies that the normalized data are within a range for subsequent calculations and that the normalized data track across the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, and the second lateral accelerometer. Operations **416** and **418** can be referred to as independent channel processing.

[0021] Operations **420** through **444** combine and correlate data from the longitudinal accelerometers, combine and correlate data from the lateral accelerometers, correct the data from the longitudinal and lateral accelerometers, and determine the velocity of and distance traveled by the vehicle, which can also be referred to as a velocity and distance integration. The system combines the longitudinal accelerometer data into a magnitude, and combines the lateral accelerometer data to create a single lateral acceleration magnitude and direction

for a determination and evaluation of cross-flow experienced by the vehicle. Specifically, beginning at operation **420**, the system uses the data from the first longitudinal accelerometer and the second longitudinal accelerometer to determine a longitudinal acceleration. At **430**, the system determines if a first acceleration is greater than a second acceleration. Referring to **FIG. 3**, the first acceleration is identified by **310**, and the second acceleration is defined by **320**. If the first acceleration is greater than the second acceleration, then the system has determined, based on the longitudinal acceleration, that an initial motion of the vehicle has commenced. Due to the accuracy and the safety requirements, two dissimilar accelerometers are used (different manufactures and different ranges) to mitigate common mode failures. The accelerometers are expected to track within a small error up to the peak of the smaller range accelerometer. In the event of a peak outside the range of the accelerometer with the lower range, the higher range accelerometer will capture the peak values. The range of the expected profile plus a margin is to be matched as closely as possible with the smaller range accelerometer. Operation **430** is basically detecting a launch or an ejection. In an embodiment, the launch or ejection may be a multiple stage event that requires an initial acceleration profile evaluation over a short time period. If an initial acceleration has not been detected, then integrator circuits that determine the velocity and distance are reset at **432**. At **434**, the system computes a longitudinal velocity of the vehicle by adding to a previously-computed velocity an average of a current acceleration and a previously-measured acceleration. This can be referred to as a rectangular integration. At **440**, the system computes a longitudinal distance of the vehicle by adding to a previously-computed distance an average of a current velocity and a previously-computed velocity. Also, at **442**, the system detects a longitudinal peak velocity and at **444**, the system detects a longitudinal velocity profile. The velocity along the longitudinal axis (or what may also be referred to as the Z-Axis) is the integration of the combination of the two longitudinal accelerometers.

[0022] Beginning at **426**, the system uses data from the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, and the second lateral accelerometer to determine a corrected longitudinal-lateral acceleration, and at **428**, to determine a longitudinal-lateral direction. The combined direction is simplified. Upon initialization a positive

direction is assumed for the X-Y sensors as their orientation to the platform is not known. The assumed direction is consistent with the sensor positive output. From this the direction may be segmented into quadrants (X+/Y+, X+/Y-, X-/Y+, Y-/Y-). The direction within each quadrant may be coarsely determined by the ratio of the X and Y magnitudes. Once determined a similar operation may be accomplished by combining the lateral direction with the longitudinal direction. Operations 426 and 428 basically combine data from the longitudinal accelerometers and data from the lateral accelerometers to create an approximated direction and magnitude of the vehicle. Given the measured acceleration, the velocity and distance are determined. At 436, the system computes a longitudinal-lateral velocity by adding to a previously-computed longitudinal-lateral velocity an average of a current longitudinal-lateral acceleration and a previously-measured longitudinal-lateral acceleration. At 440A, the system computes a longitudinal-lateral distance by adding to a previously-computed longitudinal-lateral distance an average of a current longitudinal-lateral velocity and a previously-computed longitudinal-lateral velocity. At 442A, the system detects a longitudinal-latitude peak velocity, and at 444A, the system detects a longitudinal-latitude velocity profile.

[0023] Operations 450-474 can be referred to a channel checks. At 450, the system uses the computed longitudinal distance and the computed longitudinal-lateral distance to determine if a distance traveled by the vehicle is greater than a safe separation distance. A safe separation distance is a minimum distance that a vehicle has traveled away from the launch platform before an ejection, a second stage ignition, or other function can be initiated. Specifically, double integration from the corrected acceleration is used to determine the distance from the launch platform. As noted at 450A, if the vehicle/rocket has not attained a safe separation distance, the system goes into a fail-safe mode. At 452 and 454, if a safe separation distance has been detected, that is noted by the system.

[0024] At 460, the system uses the detected longitudinal peak velocity and the detected longitudinal-lateral peak velocity to determine if the vehicle has attained a minimum velocity. In addition to verifying that the vehicle has attained a safe separation distance, it is important to verify that the vehicle has attained a minimum velocity. The minimum velocity is calculated to enable

functions that can only be successful if the object is moving above some minimum to discern the initial direction in order to be able to determine initial conditions. At 462 and 464, if a minimum velocity has been detected, that is noted by the system.

5 [0025] At 470, the system validates the longitudinal velocity profile and the longitudinal-lateral velocity profile. Profiles consist of, but are not limited to, an acceleration rate, one or more minimum acceleration peaks, an acceleration time, and an acceleration decay. These allow the system to discriminate an acceleration that has come from a functional propulsion system
10 from one that is not functioning properly or from a periodic shock that may excite the system.

[0026] At 480, after the qualifications of operations 454, 464, and 474 have been satisfied, the system initiates an action for the vehicle. That is, when the distance traveled by the vehicle is greater than a safe separation distance, the
15 peak velocity is greater than a minimum velocity threshold, and a position of the vehicle has been verified and profile data have been confirmed, the vehicular action is initiated.

Example Embodiments

20 [0027] Example No. 1 is a motion analysis system that includes an acceleration measuring device and an acceleration processor operable to detect an initial motion of a vehicle (thereby establishing a baseline); a velocity processor operable to calculate a velocity of the vehicle by adding to a previously-computed velocity an average of a current acceleration and a
25 previously-measured acceleration; a distance processor operable to calculate a distance traveled by the vehicle by adding to a previously-computed distance an average of a current velocity and a previously-computed velocity; a peak velocity processor operable to determine a peak velocity; a profile correlation processor coupled to a motion profile database, operable to verify a position of
30 the vehicle and to confirm profile data (looking for vehicle to be at certain places at certain times; precise confirmation of profile data); and a vehicle action processor operable to determine a time for an initiation of an action for the vehicle by determining that the distance traveled by the vehicle is greater than a safe separation distance and that the peak velocity is greater than a minimum

velocity threshold (e.g., rocket motor cut off deceleration; reduction in acceleration); wherein the system is configured to initiate the action for the vehicle based on the verified position of the vehicle and the confirmed profile data as determined by the profile correlation processor, and based on the

5 determination that the distance traveled by the vehicle is greater than the safe separation distance and that the peak velocity is greater than the minimum velocity as determined by the vehicle action processor.

[0028] Example No. 2 includes the features of Example No. 1, and optionally includes a system wherein the acceleration measuring device includes

10 first and second longitudinal acceleration measuring devices and first and second lateral acceleration measuring devices, wherein the first and second longitudinal acceleration measuring devices and the first and second lateral acceleration measuring devices are configured to provide acceleration data to the acceleration processor.

15 [0029] Example No. 3 includes the features of Example Nos. 1-2, and optionally includes a system wherein the acceleration processor is configured to combine data from the first and second longitudinal acceleration measuring devices, correlate the data from the first and second longitudinal acceleration measuring devices, determine if the initial motion has occurred by examining the

20 combined and correlated data from the first and second longitudinal acceleration measuring devices, and determine a longitudinal velocity, a longitudinal distance, a longitudinal peak velocity, and a longitudinal velocity profile detection based on the combined and correlated data from the first and second longitudinal acceleration measuring devices.

25 [0030] Example No. 4 includes the features of Example Nos. 1-3, and optionally includes a system wherein the acceleration processor is configured to combine and correlate data from the first and second longitudinal acceleration measuring devices and data from the first and second lateral acceleration measuring devices and determine a corrected acceleration of the vehicle, a

30 direction of the vehicle, and a velocity of the vehicle, and determine a longitudinal-lateral velocity, a longitudinal-lateral distance, a longitudinal-lateral peak velocity, and a longitudinal-lateral velocity profile detection based on the combined and correlated data from the first and second longitudinal acceleration

measuring devices and the first and second lateral acceleration measuring devices.

5 [0031] Example No. 5 includes the features of Example Nos. 1-4, and optionally includes a system configured to verify that the longitudinal velocity is not greater than the longitudinal-lateral velocity and that the longitudinal distance is not greater than the longitudinal-lateral distance, and configured to enter a fail-safe mode when the longitudinal velocity is greater than the longitudinal-lateral velocity or when the longitudinal distance is greater than the longitudinal-lateral distance.

10 [0032] Example No. 6 includes the features of Example Nos. 1-5, and optionally includes a system configured to normalize data from the first and second longitudinal acceleration measuring devices and the first and second lateral acceleration measuring devices, and a system configured to validate data ranges from the first and second longitudinal acceleration measuring devices and
15 the first and second lateral acceleration measuring devices.

[0033] Example No. 7 includes the features of Example Nos. 1-6, and optionally includes a system wherein the initiation of the action for the vehicle comprises a firing of the vehicle, a stage separation of the vehicle, a destruction of the vehicle, or a vehicle warhead function.

20 [0034] Example No. 8 includes the features of Example Nos. 1-7, and optionally includes a system including an anti-fuse field programmable gate array (FPGA) or an application specific integrated circuit (ASIC) coupled to the acceleration measuring device, wherein the anti-fuse FPGA or the ASIC includes the acceleration processor, the velocity processor, the distance
25 processor, the peak velocity processor, the profile correlation processor, and the vehicle action processor.

[0035] Example No. 9 includes the features of Example Nos. 1-8, and optionally includes a system wherein the acceleration processor, the velocity processor, the distance processor, the peak velocity processor, the profile
30 correlation processor, and the vehicle action processor include independent processors, circuits, or subsystems.

- [0036] Example No. 10 includes the features of Example Nos. 1-9, and optionally includes a system wherein the acceleration processor is operable to detect an initial launch (*e.g.*, a separation/ejection from another body) acceleration and is operable to latch (*i.e.*, detect a crossing of an acceleration threshold, for example because of motor burnout or a reduced acceleration).
- [0037] Example No. 11 includes the features of Example Nos. 1-10, and optionally includes a system wherein the profile correlation processor is operable to execute a motor/vehicle profile verification via correlation with an expected motor profile.
- 10 [0038] Example No. 12 includes the features of Example Nos. 1-11, and optionally includes a system wherein the acceleration processor is operable to sense acceleration of complex profiles in order to make ejection or launch decisions. Profiles such as previously described may also include large expected or unexpected acceleration features that with appropriate rules will dictate the response.
- 15 [0030] Example No. 13 includes the features of Example Nos. 1-12, and optionally includes a system operable to enter a fail-safe mode when the distance traveled by the vehicle is less than a safe separation distance; wherein double integration is used to calculate the distance.
- 20 [0040] Example No. 14 includes the features of Example Nos. 1-13, and optionally includes a system wherein the acceleration measuring device is operable to establish a baseline by analyzing a platform movement, an acceleration measuring device error, and an acceleration measuring device misalignment.
- 25 [0041] Example No. 15 includes the features of Example Nos. 1-14, and optionally includes a system wherein the previously-measured velocity comprises a most recently previously-measured velocity, the previously-measured acceleration comprises a most recently previously-measured acceleration, and the recently computed distance comprises a most recently
- 30 previously-computed distance; and wherein rectangular integration is used.

[0042] Example No. 16 includes the features of Example Nos. 1-15, and optionally includes a system wherein the distance processor comprises an enable circuit and a measurement circuit.

[0043] Example No. 17 includes the features of Example Nos. 1-16, and optionally includes a system wherein calculation of the velocity by the velocity processor comprises an integration of the acceleration.

[0044] Example No. 18 includes the features of Example Nos. 1-17, and optionally includes a system wherein calculation of the distance by the distance processor comprises an integration of the velocity.

[0045] Example No. 19 includes the features of Example Nos. 1-18, and optionally includes a system wherein the safe separation distance is computed to an accuracy of approximately 0.3 meters.

[0046] Example No. 20 includes the features of Example Nos. 1-19, and optionally includes a system wherein the acceleration measuring device includes a first z-axis sensor, a second z-axis sensor, an x axis sensor, and a y axis sensor, and each axis of the acceleration measuring device is processed separately.

[0047] Example No. 21 includes the features of Example Nos. 1-20, and optionally includes a system wherein the acceleration measuring device comprises an accelerometer.

[0048] Example No. 22 includes the features of Example Nos. 1-21, and optionally includes a system including a validation processor coupled to one or more of the acceleration processor, the velocity processor, the distance processor, the peak velocity processor, the profile correlation processor, and the vehicle action processor; wherein the validation processor is operable to monitor one or more of the acceleration processor, the velocity processor, the distance processor, the peak velocity processor, the profile correlation processor, and the vehicle action processor for proper operation and error detection. As described above, margins are defined for particular application in order to qualify an energetic event or stimulus.

[0049] Example No. 23 includes the features of Example Nos. 1-22, and optionally includes a system wherein the validation processor is operable to place the system into a fail-safe state when an error is detected.

[0050] Example No. 24 includes the features of Example Nos. 1-23, and optionally includes a system including a timer processor operable to determine one or more check points or wait periods (e.g., waiting to detect an action, verifying an action).

[0051] Example No. 25 is a motion analysis system for a vehicle including a first longitudinal accelerometer and a second longitudinal accelerometer; a first lateral accelerometer and a second lateral accelerometer; and a computer processor coupled to the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, and the second lateral accelerometer; wherein the computer processor is configured to execute a delay until the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, the second lateral accelerometer, and a filter stabilize; independently minimize error associated with each of the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, and the second lateral accelerometer by detecting and removing fixed offsets; normalize data received from the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, and the second lateral accelerometer; verify that the normalized data are within a range for subsequent calculations and that the normalized data track across the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, and the second lateral accelerometer; use data from the first longitudinal accelerometer and the second longitudinal accelerometer to: determine a longitudinal acceleration; determine an initial motion of the vehicle based on the longitudinal acceleration; compute a longitudinal velocity of the vehicle by adding to a previously-computed velocity an average of a current acceleration and a previously-measured acceleration; compute a longitudinal distance of the vehicle by adding to a previously-computed distance an average of a current velocity and a previously-computed velocity; detect a longitudinal peak velocity; and detect a longitudinal velocity profile; use data from the first longitudinal accelerometer, the second

longitudinal accelerometer, the first lateral accelerometer, and the second lateral
 accelerometer to: determine a corrected longitudinal-lateral acceleration;
 determine a longitudinal-lateral direction; determine a longitudinal-lateral
 distance; compute a longitudinal-lateral velocity by adding to a previously-
 5 computed longitudinal-lateral velocity an average of a current longitudinal-
 lateral acceleration and a previously-measured longitudinal-lateral acceleration;
 compute a longitudinal-lateral distance by adding to a previously-computed
 longitudinal-lateral distance an average of a current longitudinal-lateral velocity
 and a previously-computed longitudinal-lateral velocity; detect a longitudinal-
 10 latitude peak velocity; and detect a longitudinal-latitude velocity profile; use the
 computed longitudinal distance and the computed longitudinal-lateral distance to
 determine if a distance traveled by the vehicle is greater than a safe separation
 distance; use the detected longitudinal peak velocity and the detected
 longitudinal-lateral peak velocity to determine if the vehicle has attained a
 15 minimum velocity; validate the longitudinal velocity profile and the
 longitudinal-lateral velocity profile; and initiate an action for the vehicle when a
 distance traveled by the vehicle is greater than a safe separation distance, the
 peak velocity is greater than a minimum velocity threshold, and a position of the
 vehicle has been verified and profile data has been confirmed.

20 **[0052]** Example No. 26 includes the features of Example No. 25, and
 optionally includes a system wherein the computer processor, during the delay,
 verifies that one or more registers are initialized, verifies one or more clocks,
 and verifies that intelligible data are received from one or more sensors; and
 wherein the computer processor is configured to execute a second delay to
 25 measure one or more errors.

[0053] Example No. 27 includes the features of Example No. 25-26, and
 optionally includes a system wherein the detection of fixed offsets comprises
 detecting acceleration due to acceleration of the earth, an acceleration of a
 platform associated with the vehicle, (misalignment) errors associated with one
 30 or more of the first longitudinal accelerometer, the second longitudinal
 accelerometer, the first lateral accelerometer, and the second lateral
 accelerometer.

[0054] Example No. 28 includes the features of Example No. 25-27, and optionally includes a system wherein the initial motion is determined by verifying that a first acceleration is greater than a second acceleration.

[0055] Although embodiments have been described with reference to
5 specific examples, it will be evident that various modifications and changes may be made to these embodiments without departing from the broader spirit and scope of the invention. Accordingly, the specification and drawings are to be regarded in an illustrative rather than a restrictive sense. The accompanying drawings that form a part hereof, show by way of illustration, and not of
10 limitation, specific embodiments in which the subject matter may be practiced. The embodiments illustrated are described in sufficient detail to enable those skilled in the art to practice the teachings disclosed herein. Other embodiments may be utilized and derived therefrom, such that structural and logical substitutions and changes may be made without departing from the scope of this
15 disclosure. This Detailed Description, therefore, is not to be taken in a limiting sense, and the scope of various embodiments is defined only by the appended claims, along with the full range of equivalents to which such claims are entitled.

Claims

1. A motion analysis system comprising:

an acceleration measuring device and an acceleration processor operable to detect an initial motion of a vehicle;

5 a velocity processor operable to calculate a velocity of the vehicle by adding to a previously-computed velocity an average of a current acceleration and a previously-measured acceleration;

a distance processor operable to calculate a distance traveled by the vehicle by adding to a previously-computed distance an average of a
10 current velocity and a previously- computed velocity;

a peak velocity processor operable to determine a peak velocity;

a profile correlation processor coupled to a motion profile database, operable to verify a position of the vehicle and to confirm profile data; and

15 a vehicle action processor operable to determine a time for an initiation of an action for the vehicle by determining that the distance traveled by the vehicle is greater than a safe separation distance and that the peak velocity is greater than a minimum velocity threshold;

wherein the system is configured to initiate the action for the
20 vehicle based on the verified position of the vehicle and the confirmed profile data as determined by the profile correlation processor, and based on the determination that the distance traveled by the vehicle is greater than the safe separation distance and that the peak velocity is greater than the minimum velocity as determined by the vehicle action processor.

25

2. The motion analysis system of claim 1, wherein the acceleration measuring device comprises first and second longitudinal acceleration measuring devices and first and second lateral acceleration measuring devices, wherein the first and second longitudinal acceleration measuring
30 devices and the first and second lateral acceleration measuring devices are configured to provide acceleration data to the acceleration processor.

3. The motion analysis system of claim 2, wherein the acceleration processor is configured to combine data from the first and second

longitudinal acceleration measuring devices, correlate the data from the first and second longitudinal acceleration measuring devices, determine if the initial motion has occurred by examining the combined and correlated data from the first and second longitudinal acceleration measuring devices, and
5 determine a longitudinal velocity, a longitudinal distance, a longitudinal peak velocity, and a longitudinal velocity profile detection based on the combined and correlated data from the first and second longitudinal acceleration measuring devices.

10 4. The motion analysis system of claim 2, wherein the acceleration processor is configured to combine and correlate data from the first and second longitudinal acceleration measuring devices and data from the first and second lateral acceleration measuring devices and determine a corrected
15 acceleration of the vehicle, a direction of the vehicle, and a velocity of the vehicle, and determine a longitudinal-lateral velocity, a longitudinal-lateral distance, a longitudinal-lateral peak velocity, and a longitudinal-lateral velocity profile detection based on the combined and correlated data from the first and second longitudinal acceleration measuring devices and the first
20 and second lateral acceleration measuring devices.

5. The motion analysis system of claims 3 or 4, wherein the system is configured to verify that the longitudinal velocity is not greater than the longitudinal-lateral velocity and that the longitudinal distance is not greater
25 than the longitudinal-lateral distance, and the system is configured to enter a fail-safe mode when the longitudinal velocity is greater than the longitudinal-lateral velocity or when the longitudinal distance is greater than the longitudinal-lateral distance.

30 6. The motion analysis system of claim 2, wherein the system is configured to normalize data from the first and second longitudinal acceleration measuring devices and the first and second lateral acceleration measuring devices, and the system is configured to validate data ranges from the first and second longitudinal acceleration measuring devices and the first and
35 second lateral acceleration measuring devices.

- 5 7. The motion analysis system of claim 1, wherein the acceleration processor is operable to detect an initial launch acceleration and is operable to detect a crossing of an acceleration threshold.
- 10 8. The motion analysis system of claim 1, wherein the profile correlation processor is operable to execute a motor profile verification via correlation with an expected motor profile.
- 15 9. The motion analysis system of claim 1, wherein the acceleration processor is operable to sense acceleration of complex profiles in order to make eject or launch decisions.
- 20 10. The motion analysis system of claim 1, wherein the motion analysis system is operable to enter a fail-safe mode when the distance traveled by the vehicle is less than a safe separation distance.
- 25 11. The motion analysis system of claim 1, wherein the acceleration measuring device is operable to establish a baseline by analyzing a platform movement, an acceleration measuring device error, and an acceleration measuring device misalignment.
- 30 12. The motion analysis system of claim 1, wherein the safe separation distance is computed to an accuracy of approximately 0.3 meters.
- 35 13. The motion analysis system of claim 1, wherein the acceleration measuring device comprises a first z-axis sensor, a second z-axis sensor, an x axis sensor, and a y axis sensor, and each axis of the acceleration measuring device is processed separately.
14. The motion analysis system of claim 1, comprising a validation processor coupled to one or more of the acceleration processor, the velocity processor, the distance processor, the peak velocity processor, the profile correlation processor, and the vehicle action processor; wherein the validation processor is operable to monitor one or more of the acceleration processor, the velocity

processor, the distance processor, the peak velocity processor, the profile correlation processor, and the vehicle action processor for proper operation and error detection.

5 15. The motion analysis system of claim 1, comprising a timer processor operable to determine one or more check points or wait periods.

16. A motion analysis system for a vehicle comprising:

10 a first longitudinal accelerometer and a second longitudinal accelerometer;

a first lateral accelerometer and a second lateral accelerometer;
and

15 a computer processor coupled to the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, and the second lateral accelerometer;

wherein the computer processor is configured to:

execute a delay until the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, the second lateral accelerometer, and a filter stabilize;

20 independently minimize error associated with each of the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, and the second lateral accelerometer by detecting and removing fixed offsets;

25 normalize data received from the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, and the second lateral accelerometer;

30 verify that the normalized data are within a range for subsequent calculations and that the normalized data track across the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, and the second lateral accelerometer;

use data from the first longitudinal accelerometer and the second longitudinal accelerometer to:

determine a longitudinal acceleration;

5 determine an initial motion of the vehicle based on the longitudinal acceleration;

compute a longitudinal velocity of the vehicle by adding to a previously-computed velocity an average of a current acceleration and a previously-measured acceleration;

10 compute a longitudinal distance of the vehicle by adding to a previously-computed distance an average of a current velocity and a previously-computed velocity;

detect a longitudinal peak velocity; and

detect a longitudinal velocity profile;

15 use data from the first longitudinal accelerometer, the second longitudinal accelerometer, the first lateral accelerometer, and the second lateral accelerometer to:

determine a corrected longitudinal-lateral acceleration;

determine a longitudinal-lateral direction;

20 determine a longitudinal-lateral distance;

compute a longitudinal-lateral velocity by adding to a previously-computed longitudinal-lateral velocity an average of a current longitudinal-lateral acceleration and a previously-measured longitudinal-lateral acceleration;

25 compute a longitudinal-lateral distance by adding to a previously-computed longitudinal-lateral distance an average of a current longitudinal-lateral velocity and a previously-computed longitudinal-lateral velocity;

detect a longitudinal-latitude peak velocity; and

detect a longitudinal-latitude velocity profile;

use the computed longitudinal distance and the computed longitudinal-lateral distance to determine if a distance traveled by the vehicle is greater than a safe separation distance;

5 use the detected longitudinal peak velocity and the detected longitudinal-lateral peak velocity to determine if the vehicle has attained a minimum velocity;

validate the longitudinal velocity profile and the longitudinal-lateral velocity profile; and

10 initiate an action for the vehicle when a distance traveled by the vehicle is greater than a safe separation distance, the peak velocity is greater than a minimum velocity threshold, and a position of the vehicle has been verified and profile data have been confirmed.

15 17. The motion analysis system of claim 16, wherein the computer processor, during the delay, verifies that one or more registers are initialized, verifies one or more clocks, and verifies that intelligible data are received from one or more sensors; and wherein the computer processor is configured to execute a second delay to measure one or more errors.

20 18. The motion analysis system of claim 16, wherein the detection of fixed offsets comprises detecting acceleration due to acceleration of the earth, an acceleration of a platform associated with the vehicle, and misalignment errors associated with one or more of the first longitudinal accelerometer, the
25 second longitudinal accelerometer, the first lateral accelerometer, and the second lateral accelerometer.

30 19. The motion analysis system of claim 16, wherein the initial motion is determined by verifying that a second acceleration is greater than a first acceleration.

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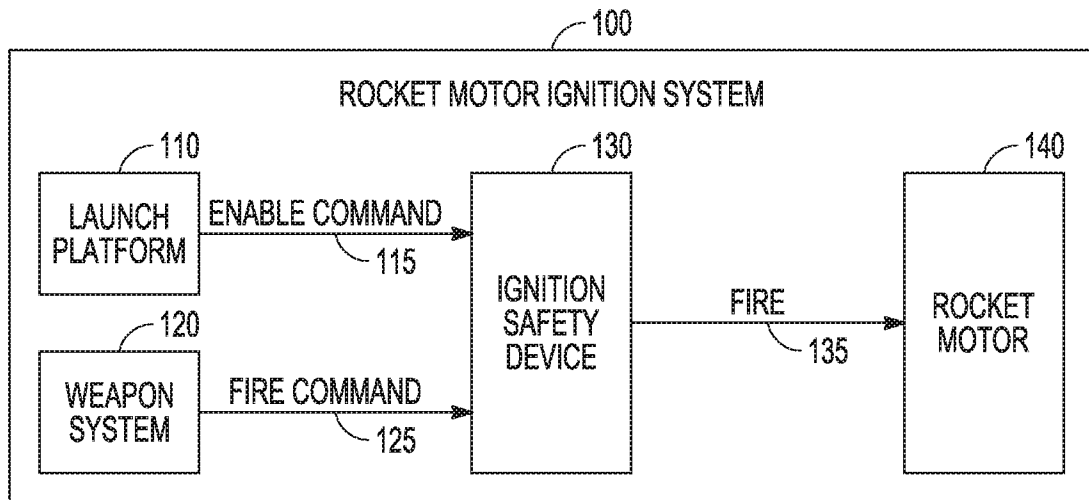


FIG. 1

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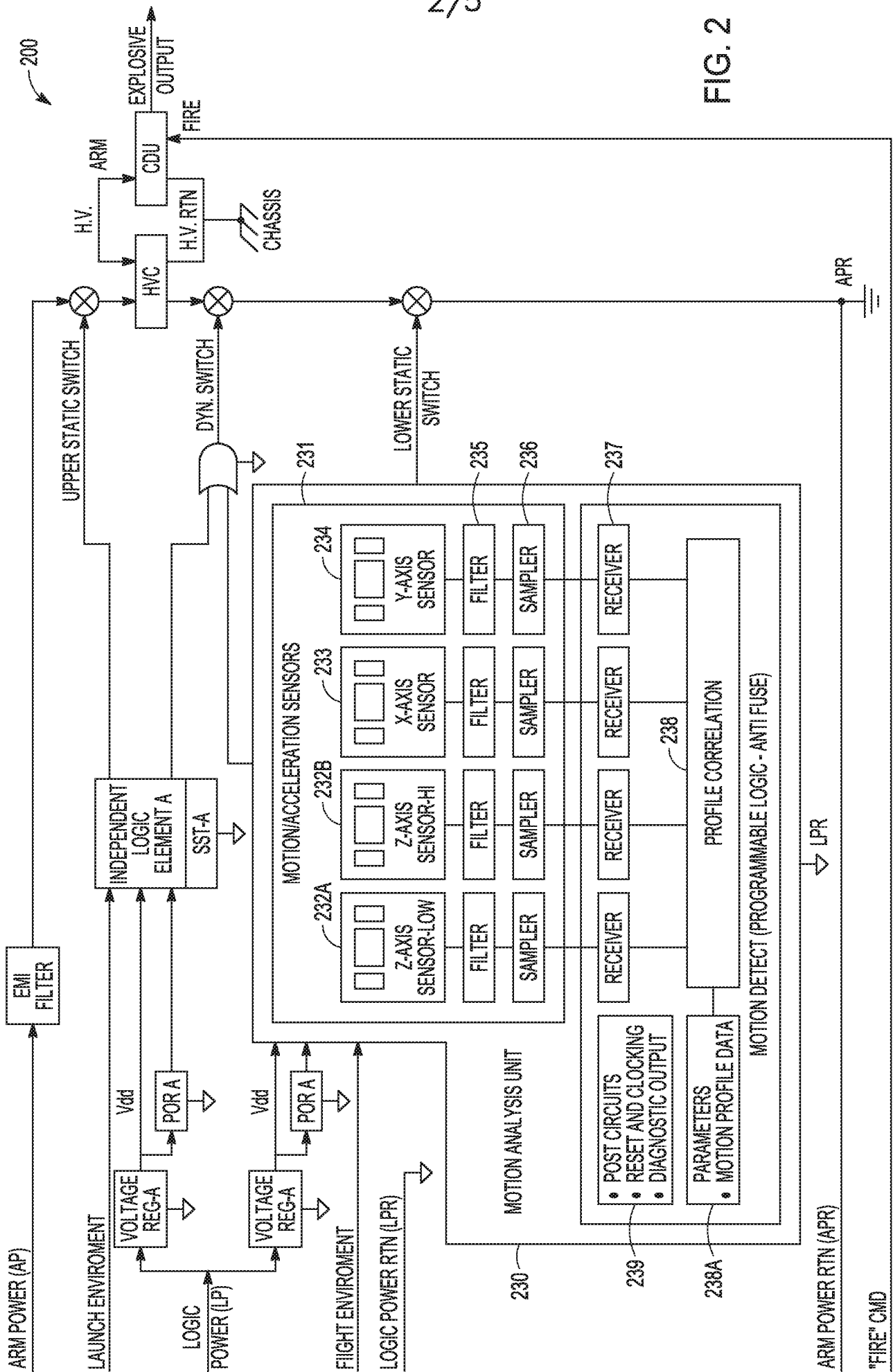


FIG. 2

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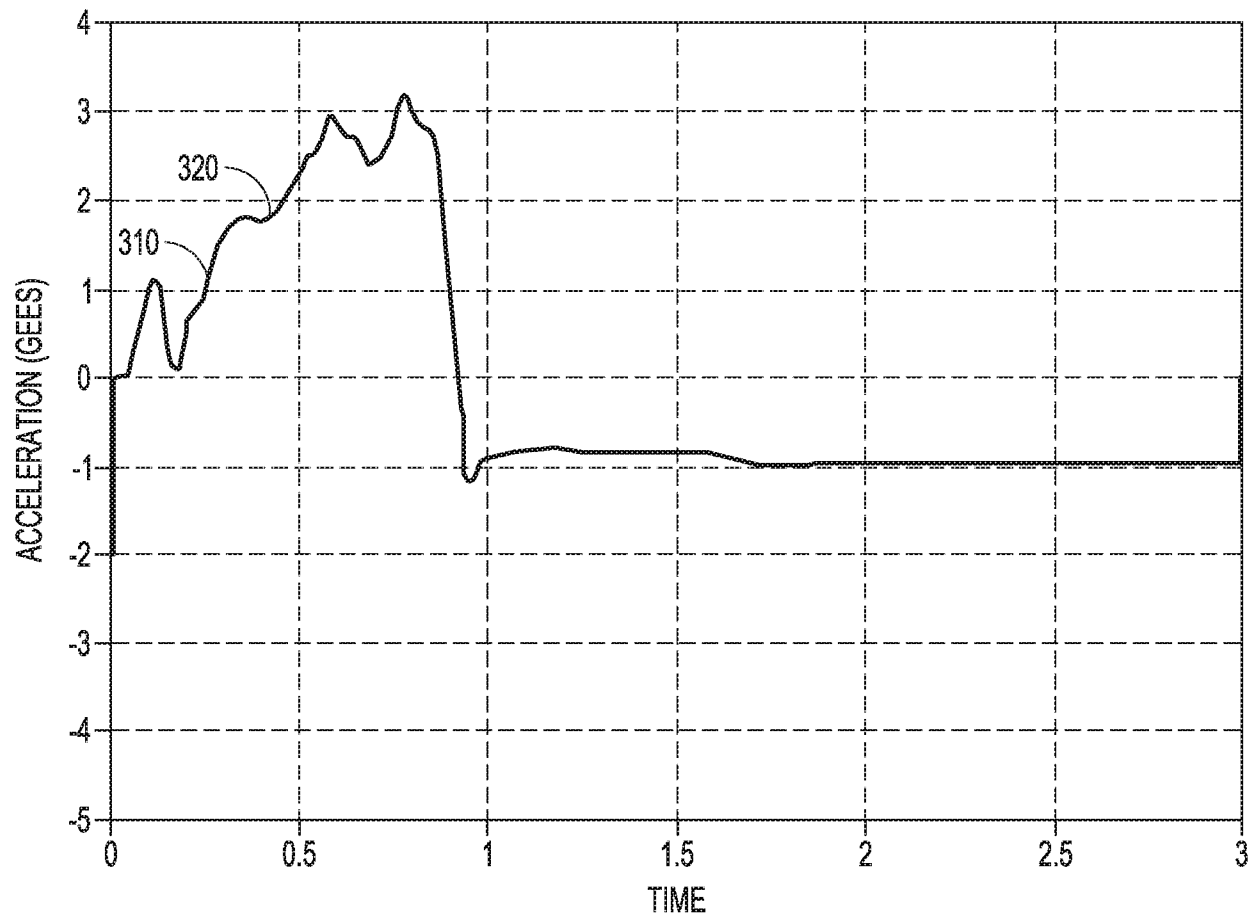


FIG. 3

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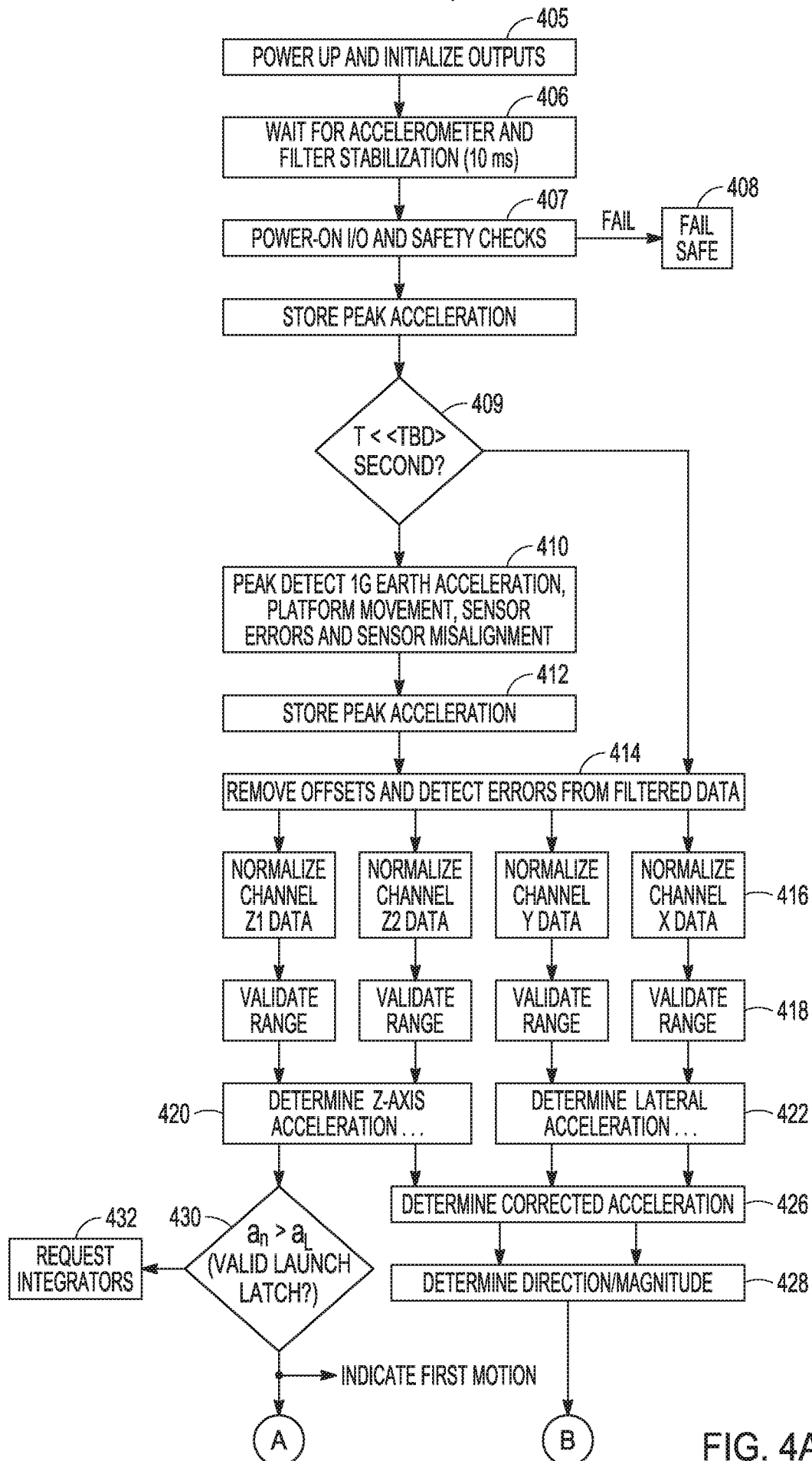


FIG. 4A

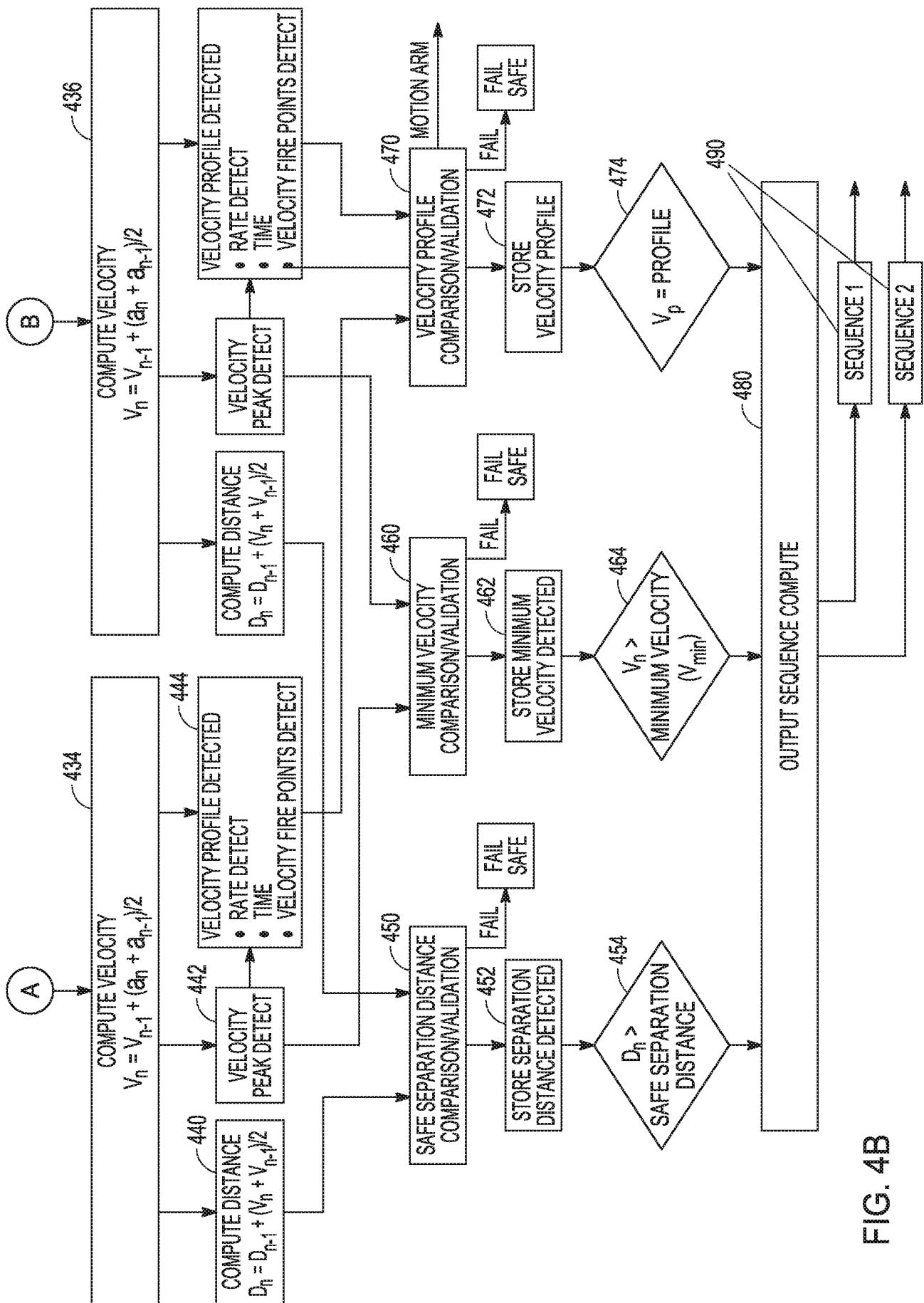


FIG. 4B

INTERNATIONAL SEARCH REPORT		International application No. PCT/US17/47765		
A. CLASSIFICATION OF SUBJECT MATTER IPC: F41G 7/00(2006.01),9/00(2006.01) CPC: G01C 23/00, 23/005; G08G 5/0021, 5/0013, 5/0052 According to International Patent Classification (IPC) or to both national classification and IPC				
B. FIELDS SEARCHED				
Minimum documentation searched (classification system followed by classification symbols) CPC : G01C 23/00, 23/005; G08G 5/0021, 5/0013, 5/0052				
Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched				
Electronic data base consulted during the international search (name of data base and, where practicable, search terms used)				
C. DOCUMENTS CONSIDERED TO BE RELEVANT				
Category *	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.		
A	US 2010/0209886 A1 ((LIN et al.) 19 August 2010, see entire document.	1-19		
A	US 2010/0209891 A1 (LIN et al.) 19 August 2010, see entire document.	1-19		
☐ Further documents are listed in the continuation of Box C. ☐ See patent family annex.				
<table style="width: 100%; border: none;"> <tr> <td style="width: 50%; vertical-align: top;"> * Special categories of cited documents: "A" document defining the general state of the art which is not considered to be of particular relevance "E" earlier application or patent published on or after the international filing date "L" document which may throw doubts on priority claim(s) or which is cited to establish the publication date of another citation or other special reason (as specified) "O" document referring to an oral disclosure, use, exhibition or other means "P" document published prior to the international filing date but later than the priority date claimed </td> <td style="width: 50%; vertical-align: top;"> "T" later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention "X" document of particular relevance; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone "Y" document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art "&" document member of the same patent family </td> </tr> </table>			* Special categories of cited documents: "A" document defining the general state of the art which is not considered to be of particular relevance "E" earlier application or patent published on or after the international filing date "L" document which may throw doubts on priority claim(s) or which is cited to establish the publication date of another citation or other special reason (as specified) "O" document referring to an oral disclosure, use, exhibition or other means "P" document published prior to the international filing date but later than the priority date claimed	"T" later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention "X" document of particular relevance; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone "Y" document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art "&" document member of the same patent family
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Date of the actual completion of the international search 11 March 2018 (11.03.2018)		Date of mailing of the international search report 16 MAR 2018		
Name and mailing address of the ISA/US Mail Stop PCT, Attn: ISA/US Commissioner for Patents P.O. Box 1450 Alexandria, Virginia 22313-1450 Facsimile No. (571) 273-8300		Authorized officer Harry Kim Telephone No. 571-272-4300		