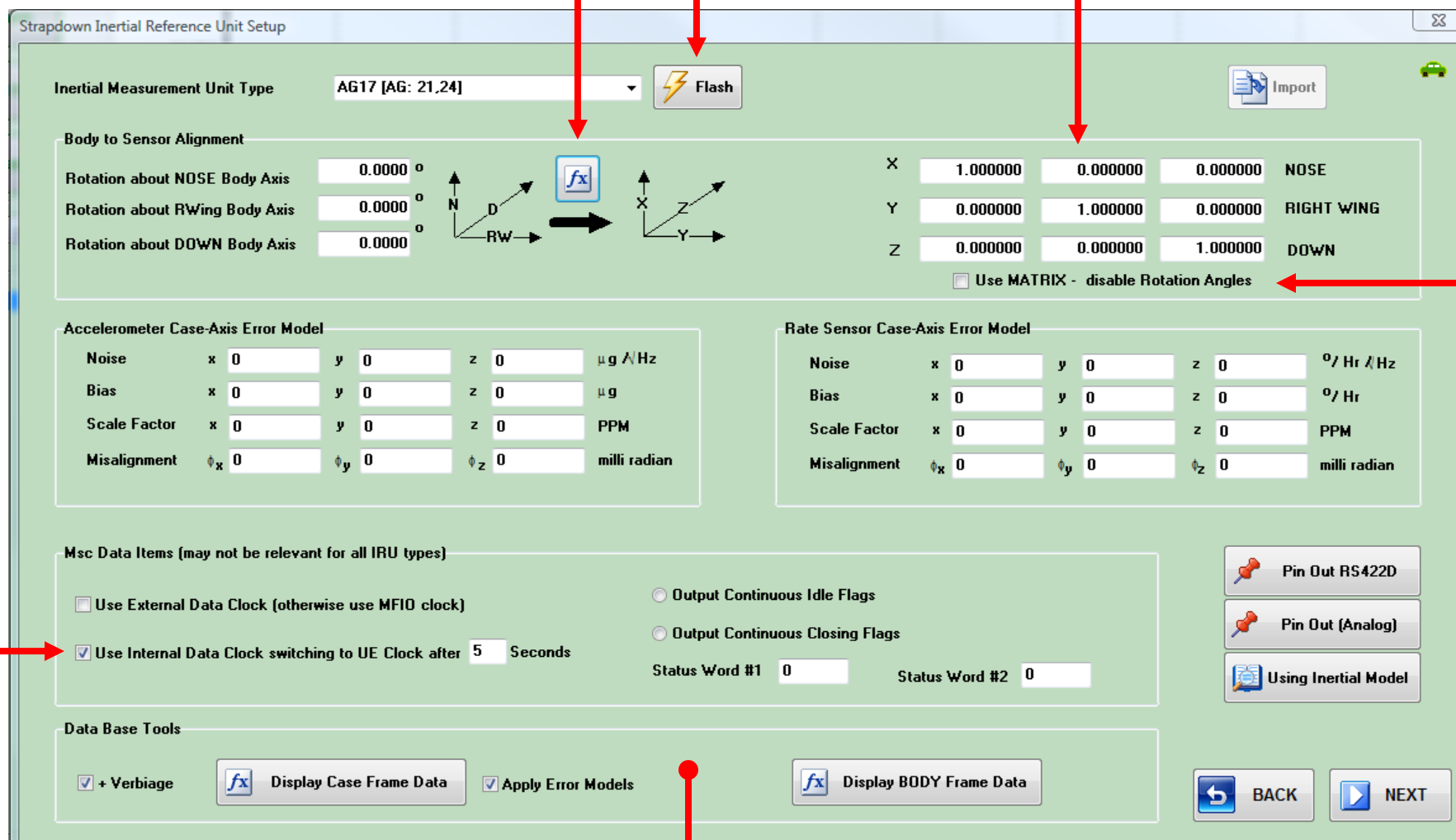


This is the attached Matrix Convention document

Flash the IMU.
No more batch files.

You can enter the MATRIX you define
and over-ride my method



The screenshot shows the 'Strapdown Inertial Reference Unit Setup' window. Red arrows point to the following elements:

- Matrix Convention document:** Points to the 'fx' icon in the 'Body to Sensor Alignment' section.
- Flash the IMU:** Points to the 'Flash' button (lightning bolt icon).
- Matrix input:** Points to the 'MATRIX' input fields (X, Y, Z) and the 'Use MATRIX - disable Rotation Angles' checkbox.
- Clock delay:** Points to the 'Use Internal Data Clock switching to UE Clock after 5 Seconds' checkbox in the 'Msc Data Items' section.
- ASCII data files:** Points to the 'Display Case Frame Data' button in the 'Data Base Tools' section.

Body to Sensor Alignment

Rotation about	Angle	Unit
NOSE Body Axis	0.0000	°
RWing Body Axis	0.0000	°
DOWN Body Axis	0.0000	°

Acceleration Case-Axis Error Model

Parameter	x	y	z	Unit
Noise	0	0	0	$\mu\text{g}/\text{Hz}$
Bias	0	0	0	μg
Scale Factor	0	0	0	PPM
Misalignment	ϕ_x 0	ϕ_y 0	ϕ_z 0	milli radian

Rate Sensor Case-Axis Error Model

Parameter	x	y	z	Unit
Noise	0	0	0	$^{\circ}/\text{Hr}/\text{Hz}$
Bias	0	0	0	$^{\circ}/\text{Hr}$
Scale Factor	0	0	0	PPM
Misalignment	ϕ_x 0	ϕ_y 0	ϕ_z 0	milli radian

Msc Data Items (may not be relevant for all IRU types)

☐ Use External Data Clock (otherwise use MFIO clock)

☒ Use Internal Data Clock switching to UE Clock after 5 Seconds

☐ Output Continuous Idle Flags

☐ Output Continuous Closing Flags

Status Word #1: 0 Status Word #2: 0

Data Base Tools

☒ + Verbiage ☒ Display Case Frame Data ☒ Apply Error Models ☒ Display BODY Frame Data

Buttons: Pin Out RS422D, Pin Out (Analog), Using Inertial Model, BACK, NEXT

This is the Clock delay CUBIC needs. We found the associated firmware and are converting it to the new MFIO

This will produce ASCII data files that provide time tagged engineer output. (for analysis only)