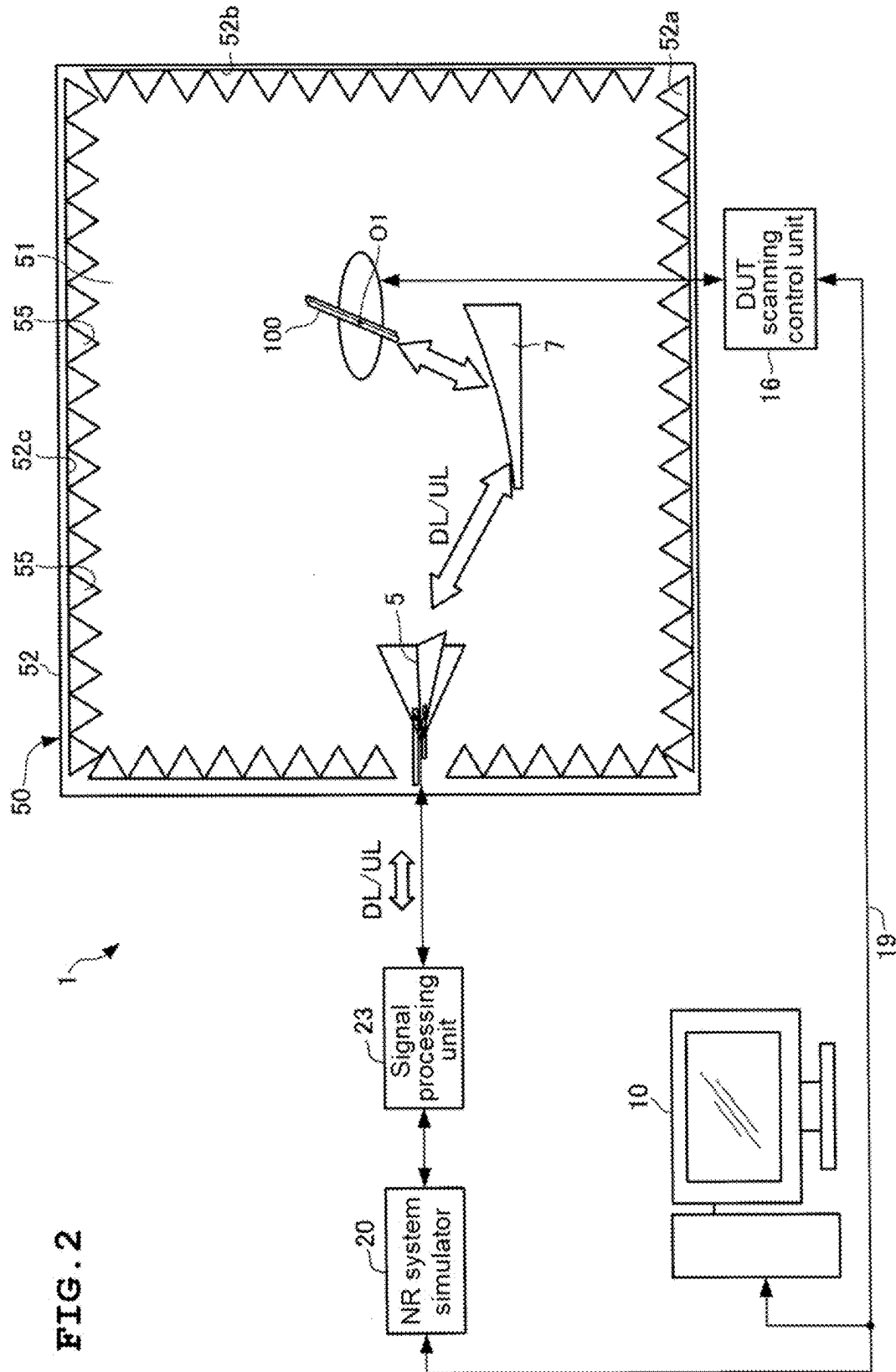
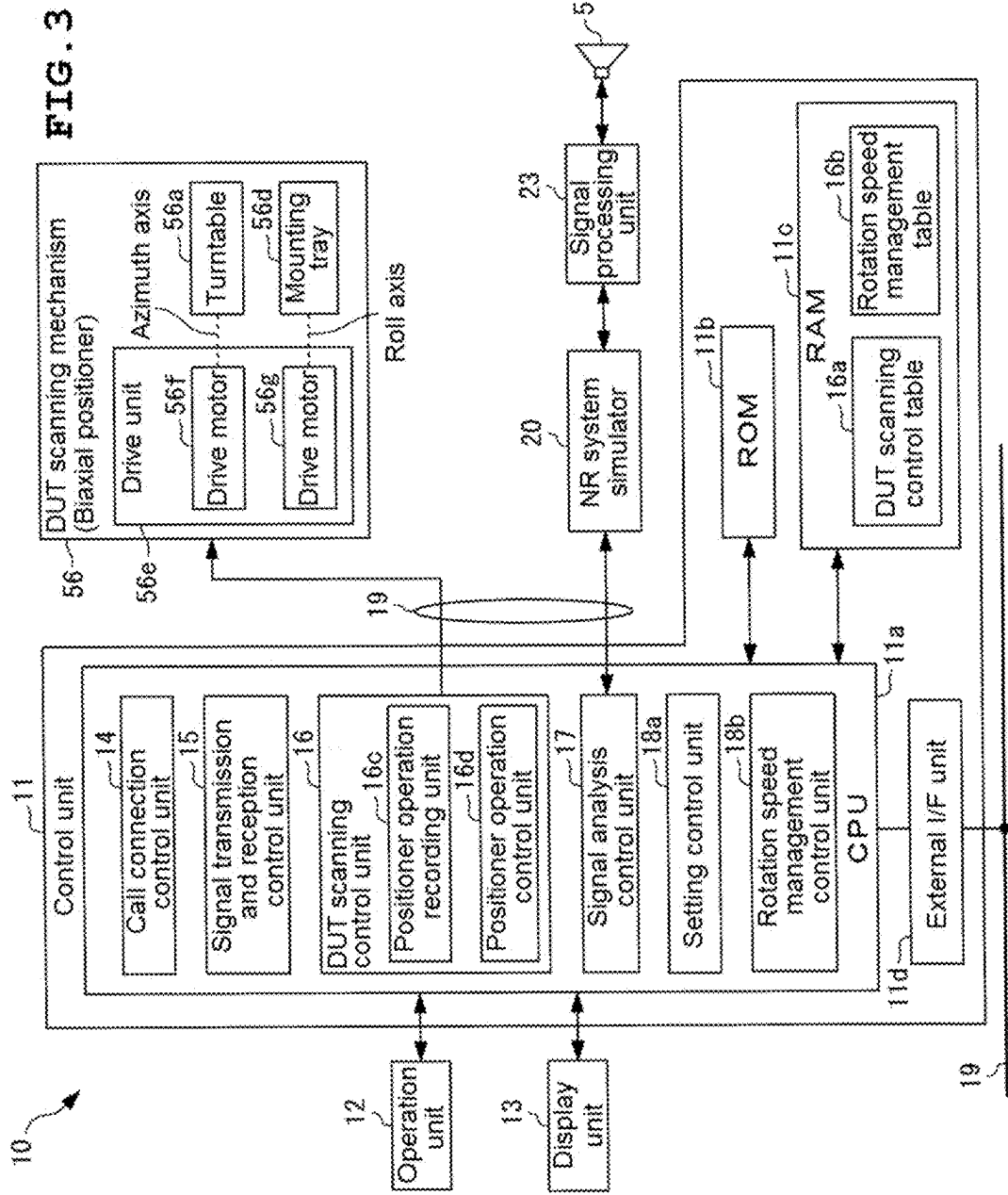


FIG. 1





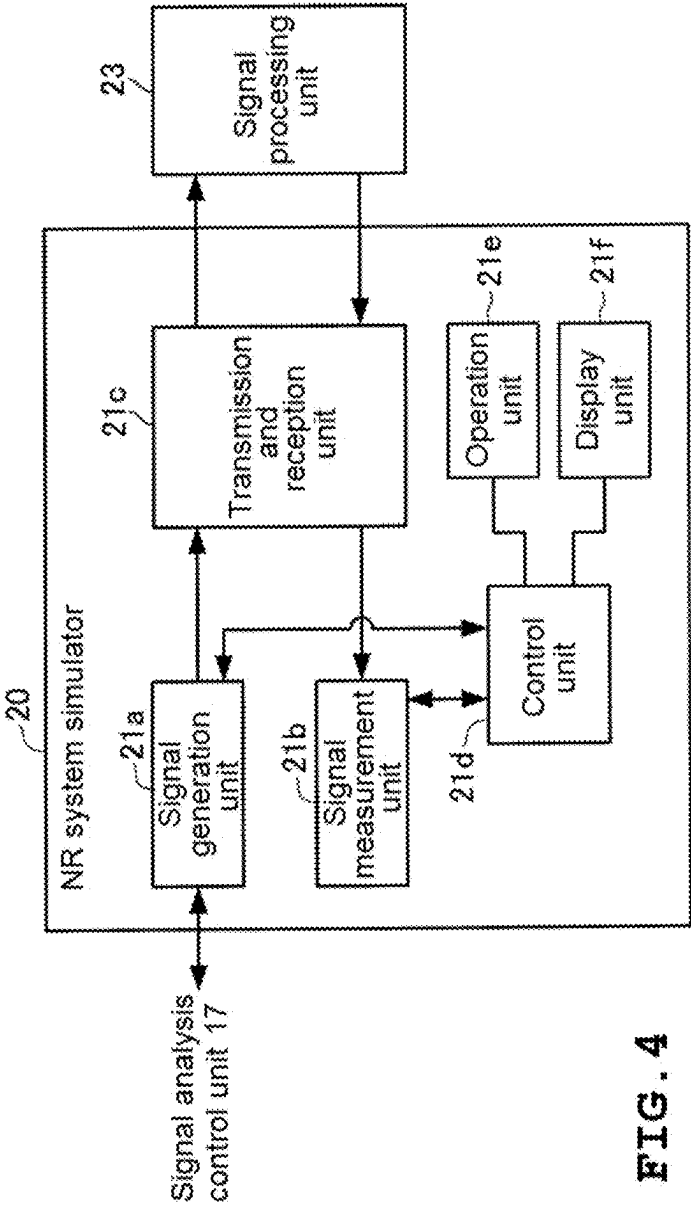


FIG. 4

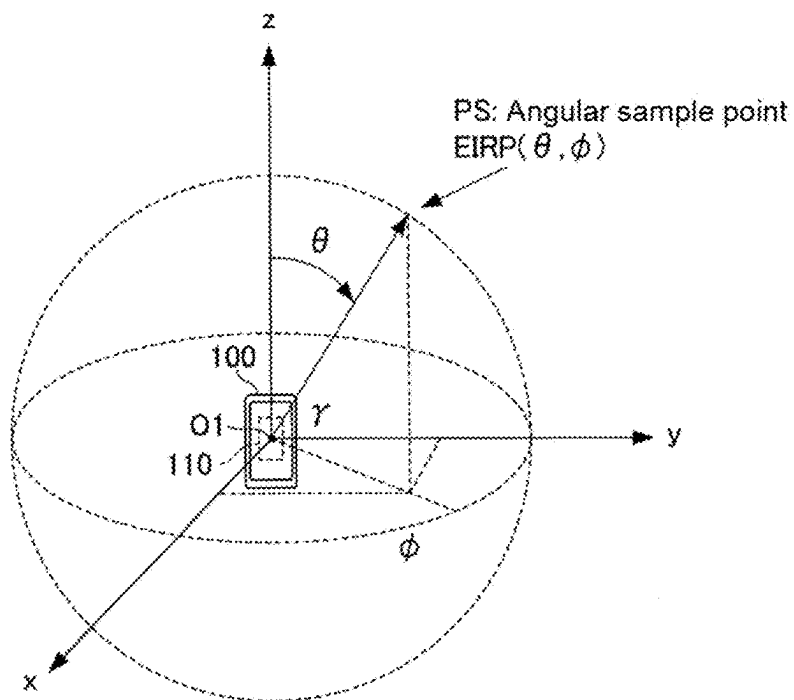


FIG. 5A

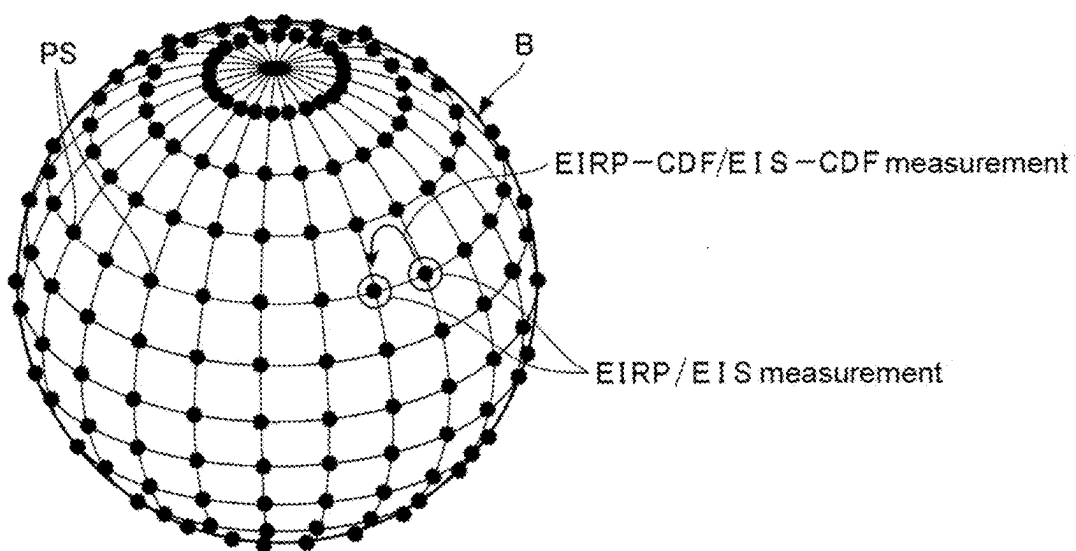


FIG. 5B

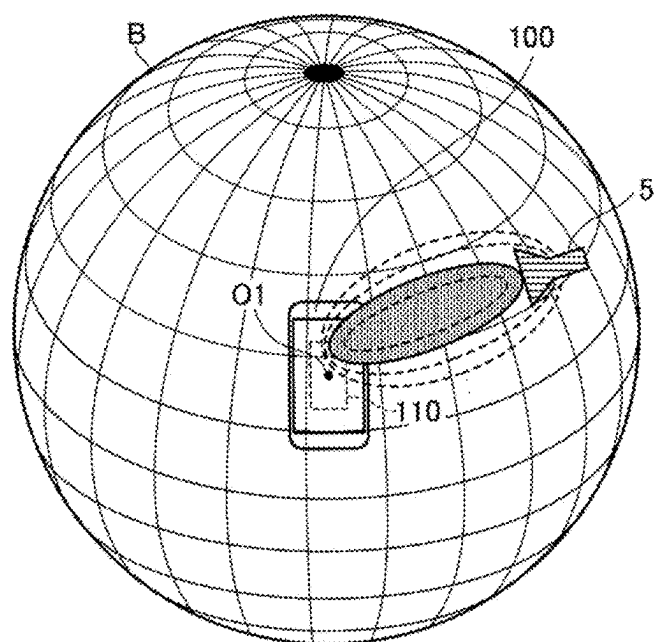


FIG. 6

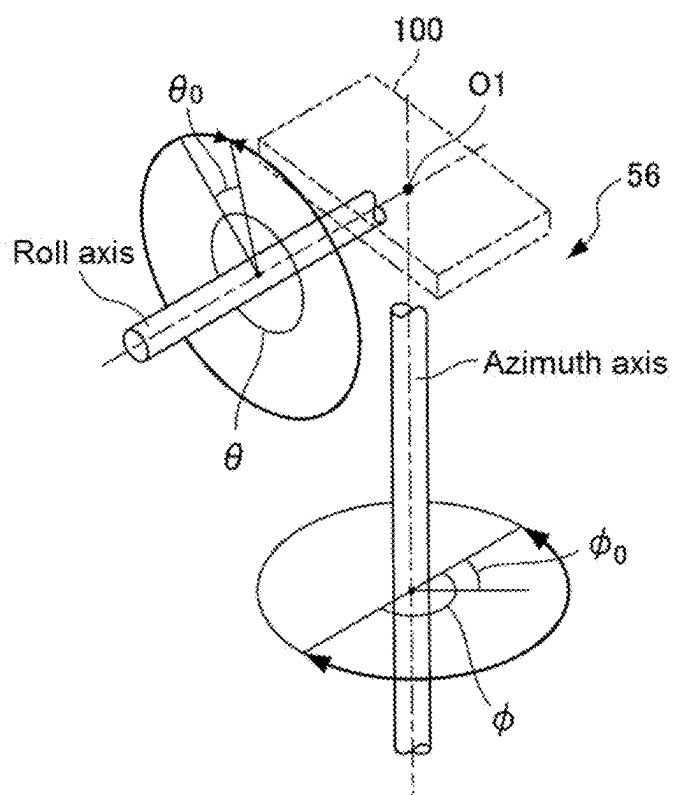


FIG. 7

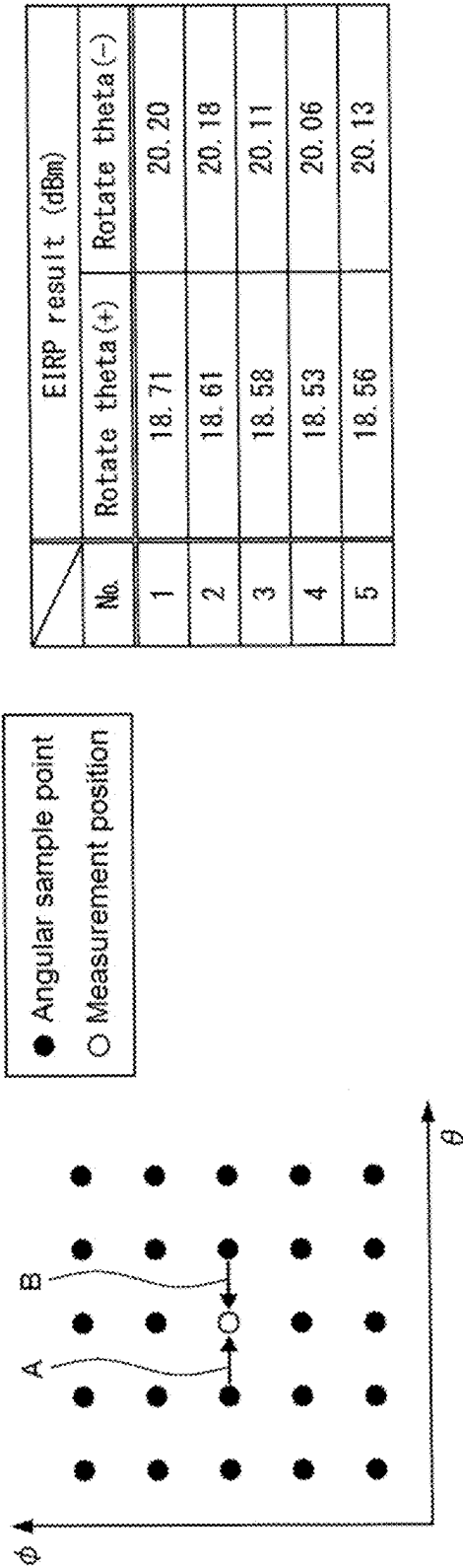
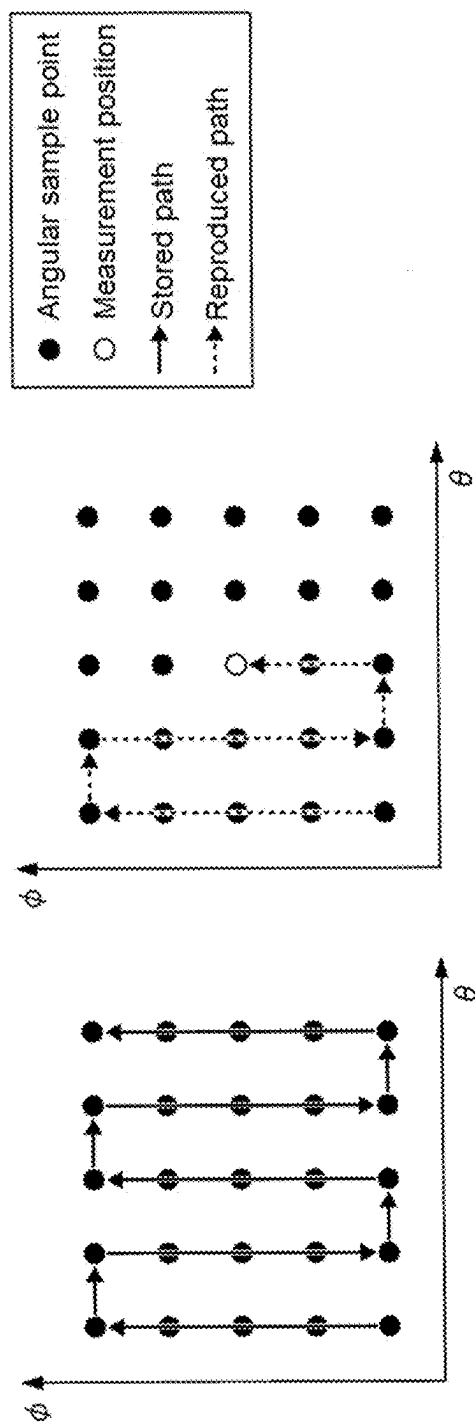


FIG. 8



MOBILE TERMINAL TESTING DEVICE AND MOBILE TERMINAL TESTING METHOD

TECHNICAL FIELD

[0001] The present invention relates to a mobile terminal testing device that tests a mobile terminal by exchanging signals while changing an angle of a positioner on which the mobile terminal is installed under an Over The Air (OTA) environment.

BACKGROUND ART

[0002] For a wireless terminal that has been developed in recent years and transmits and receives a radio signal corresponding to IEEE802.11ad, 5G cellular, and the like, in which a signal in a wide band of a millimeter wave band is used, a performance test is performed of measuring an output level and reception sensitivity of a transmitted radio wave determined for each communication standard with respect to a wireless communication antenna included in the wireless terminal, and determining whether or not a predetermined reference is satisfied.

[0003] For example, in a performance test in which a wireless terminal (hereinafter, referred to as a “5G wireless terminal”) for a New Radio System (NR system) of a fifth generation mobile communication system (hereinafter, also referred to as “5G”) is used as a Device Under Test (DUT), an OTA test using an anechoic box (OTA chamber) referred to as a Compact Antenna Test Range (CATR) that is not affected by a surrounding radio wave environment is performed.

[0004] As an example of a wireless terminal measurement device according to the related art capable of performing an OTA test, it is known that a wireless terminal is rotated around a reference point in a measurement space such as an anechoic box or an anechoic chamber, while radio waves transmitted from the wireless terminal are received by a measurement antenna, and radiation power characteristics (such as Equivalent Isotropic Radiated Power (EIRP), Equivalent Isotropic Sensitivity (EIS), Total Radiated Power (TRP)) of the wireless terminal are obtained from the received signal.

[0005] Patent Document 1 describes that, in the measurement of the DUT that is rotated to sequentially face all orientations of the spherical coordinate system under the OTA environment, the progress of the measurement at each measurement position is displayed.

RELATED ART DOCUMENT

[Patent Document]

[0006] [Patent Document 1] Japanese Patent No. 7227198

DISCLOSURE OF THE INVENTION

Problem that the Invention is to Solve

[0007] Measurements in the OTA environment are performed while changing the angle of the positioner on which the DUT is installed. However, it was found that the behavior of the antenna control on the DUT side, and the like changes depending on the operation path of the positioner to the measurement position, resulting in different measurement results.

[0008] Therefore, an object of the present invention is to provide a mobile terminal testing device that can improve measurement reproducibility at the same measurement position by reproducing the operation path of the positioner to the measurement position.

Means for Solving the Problem

[0009] According to the present invention, there is provided a mobile terminal testing device including: a positioner that is provided in an internal space of an anechoic box, has an azimuth axis and a roll axis that are each rotationally drivable by a drive motor, and rotates a mobile terminal that is a device under test so that the mobile terminal sequentially faces a plurality of preset angular sample points of a spherical coordinate system, using a center of the spherical coordinate system as a reference point; a simulated measurement device connected to a test antenna in the internal space; an integrated control device that controls the simulated measurement device so that a measurement operation of transmitting a test signal from the test antenna to the mobile terminal, receiving a signal under measurement transmitted from the mobile terminal that has received the test signal by using the test antenna, and measuring a specific measurement item related to the mobile terminal based on the received signal under measurement is performed at a measurement position corresponding to each of the plurality of angular sample points; and a positioner operation recording unit that stores an operation path of the positioner to the measurement position by tracing back from the measurement position to a preset number of the angular sample points; and a positioner operation control unit that controls the positioner according to the operation path stored in the positioner operation recording unit to adjust the mobile terminal to an angle of the measurement position when performing measurement at the measurement position.

[0010] With this configuration, the operation path to the measurement position is stored by tracing back from the measurement position to a preset number of angular sample points, and the mobile terminal is adjusted to the angle of the measurement position according to the stored path when performing measurement at the measurement position. Therefore, measurement reproducibility at the same measurement position can be improved.

[0011] In the mobile terminal testing device according to the present invention, the positioner operation recording unit stores different operation paths up to a preset number in a case where the operation path of the positioner to the measurement position is an operation path different from the stored operation path.

[0012] With this configuration, in a case where the operation path to the measurement position is an operation path different from the stored operation path, different operation paths are stored up to a preset number. Therefore, measurement reproducibility at the same measurement position can be improved.

[0013] In addition, according to the present invention, there is provided a mobile terminal testing method of a mobile terminal testing device including a positioner that is provided in an internal space of an anechoic box, has an azimuth axis and a roll axis that are each rotationally drivable by a drive motor, and rotates a mobile terminal that is a device under test so that the mobile terminal sequentially faces a plurality of preset angular sample points of a spherical coordinate system, using a center of the spherical

coordinate system as a reference point, a simulated measurement device connected to a test antenna in the internal space, and an integrated control device that controls the simulated measurement device so that a measurement operation of transmitting a test signal from the test antenna to the mobile terminal, receiving a signal under measurement transmitted from the mobile terminal that has received the test signal by using the test antenna, and measuring a specific measurement item related to the mobile terminal based on the received signal under measurement is performed at a measurement position corresponding to each of the plurality of angular sample points, the mobile terminal testing method including: a step of storing an operation path of the positioner to the measurement position by tracing back from the measurement position to a preset number of the angular sample points; and a step of controlling the positioner according to the stored operation path to adjust the mobile terminal to an angle of the measurement position when performing measurement at the measurement position.

[0014] In the mobile terminal testing method according to the present invention, the step of storing the operation path of the positioner is a step of storing different operation paths up to a preset number in a case where the operation path of the positioner to the measurement position is an operation path different from the stored operation path.

[0015] With this configuration, the operation path to the measurement position is stored by tracing back from the measurement position to a preset number of angular sample points, and the mobile terminal is adjusted to the angle of the measurement position according to the stored path when performing measurement at the measurement position. Therefore, measurement reproducibility at the same measurement position can be improved.

Advantage of the Invention

[0016] The present invention can provide a mobile terminal testing device that can improve measurement reproducibility at the same measurement position.

BRIEF DESCRIPTION OF THE DRAWINGS

[0017] FIG. 1 is a diagram showing a schematic configuration of an entire measurement device according to an embodiment of the present invention.

[0018] FIG. 2 is a block diagram showing a functional configuration of the measurement device according to the embodiment of the present invention.

[0019] FIG. 3 is a block diagram showing functional configurations of an integrated control device of the measurement device and a controlled system element thereof according to the embodiment of the present invention.

[0020] FIG. 4 is a block diagram showing a functional configuration of an NR system simulator in the measurement device according to the embodiment of the present invention.

[0021] FIGS. 5A and 5B are diagrams showing total spherical scanning images of a device under test in an OTA chamber of the measurement device according to the embodiment of the present invention, in which FIG. 5A shows a disposition mode of the device under test with respect to a center of a spherical coordinate system, and FIG. 5B shows a distribution mode of angular sample points PS in the spherical coordinate system.

[0022] FIG. 6 is a diagram explaining a disposition mode of a test antenna 5 in the OTA chamber of the measurement device according to the embodiment of the present invention using the spherical coordinate system (r, θ, φ) shown in FIGS. 5A and 5B.

[0023] FIG. 7 is a diagram showing a rotation drive image around an azimuth axis and a roll axis of a biaxial positioner related to the total spherical scanning of the DUT in the measurement device according to the embodiment of the present invention.

[0024] FIG. 8 is a diagram showing an example of measurement results based on paths to a measurement position of the measurement device according to the embodiment of the present invention.

[0025] FIG. 9 is a diagram showing an example of path reproduction to the measurement position of the measurement device according to the embodiment of the present invention.

BEST MODE FOR CARRYING OUT THE INVENTION

[0026] Hereinafter, a measurement device as a mobile terminal testing device according to an embodiment of the present invention will be described with reference to the drawings.

[0027] First, a configuration of a measurement device 1 according to the embodiment of the present invention will be described with reference to FIGS. 1 to 4. The measurement device 1 constitutes the mobile terminal testing device of the present invention. The measurement device 1 according to the present embodiment has an external structure as shown in FIG. 1 as a whole, and includes functional blocks as shown in FIG. 2. FIGS. 1 and 2 show a disposition mode of each component of an OTA chamber 50 in a state of being seen through from a side surface thereof.

[0028] The measurement device 1 is operated, for example, in a mode in which each of the above-described components is mounted on each rack 90a of a rack structure 90 having the structure shown in FIG. 1. FIG. 1 shows an example in which each of an integrated control device 10, an NR system simulator 20, and an OTA chamber 50 is mounted on each rack 90a of the rack structure 90.

[0029] As shown in FIG. 2, the measurement device 1 includes the integrated control device 10, the NR system simulator 20, a signal processing unit 23, and the OTA chamber 50.

[0030] For the configuration, the OTA chamber 50 will be described first. As shown in FIGS. 1 and 2, the OTA chamber 50 includes, for example, a metal housing main body 52 having a rectangular internal space 51, and accommodates a DUT 100 having an antenna 110, a test antenna 5, a reflector 7, and a DUT scanning mechanism 56 in the internal space 51.

[0031] A radio wave absorber 55 is attached to a whole area of an inner surface of the OTA chamber 50, that is, a bottom surface 52a, a side surface 52b, and a top surface 52c of the housing main body 52. As a result, in the OTA chamber 50, each element (the DUT 100, the test antenna 5, the reflector 7, and the DUT scanning mechanism 56) disposed in the internal space 51 has an enhanced function of regulating intrusion of radio waves from the outside and radiation of the radio waves to the outside. In this way, the OTA chamber 50 realizes an anechoic box having the internal space 51 that is not affected by a surrounding radio

wave environment. The anechoic box used in the present embodiment is, for example, an anechoic type.

[0032] Among those accommodated in the internal space 51 of the OTA chamber 50, the DUT 100 is, for example, a wireless terminal such as a smartphone. Communication standards for the DUT 100 include cellular (LTE, LTE-A, W-CDMA (registered trademark), GSM (registered trademark), CDMA 2000, 1×EV-DO, TD-SCDMA, or the like), wireless LAN (IEEE 802.11b/g/a/n/ac/ad, or the like), Bluetooth (registered trademark), GNSS (GPS, Galileo, GLO-NASS, BeiDou, or the like), FM, and digital broadcasting (DVB-H, ISDB-T, or the like). Further, the DUT 100 may be a wireless terminal that transmits and receives a radio signal in a millimeter wave band corresponding to IEEE 802.11ad, 5G cellular, or the like.

[0033] In the present embodiment, the antenna 110 of the DUT 100 uses a radio signal in each regulated frequency band in conformity with, for example, LTE or 5G NR communication standard. The DUT 100 constitutes the device under test, that is, a mobile terminal in the present invention.

[0034] In the internal space 51 of the OTA chamber 50, the DUT 100 is held by a part of mechanism of the DUT scanning mechanism 56. The DUT scanning mechanism 56 is provided to extend in a vertical direction on the bottom surface 52a of the housing main body 52 in the internal space 51 of the OTA chamber 50. The DUT scanning mechanism 56 performs a total spherical scanning (refer to FIGS. 5A and 5B and FIG. 6), which will be described later, on the DUT 100 while holding the DUT 100 on which a performance test is performed.

[0035] As shown in FIG. 1, the DUT scanning mechanism 56 includes a turntable 56a, a support column member 56b, a DUT mounting portion 56c, and a drive unit 56e. The turntable 56a includes a plate member having a disk shape, and has a configuration (refer to FIG. 3 and FIG. 7) that rotates around an azimuth axis (a rotation axis in the vertical direction). The support column member 56b includes a columnar member disposed to extend in a direction perpendicular to a plate surface of the turntable 56a.

[0036] The DUT mounting portion 56c is disposed near an upper end of the support column member 56b to be in parallel with the turntable 56a, and has a mounting tray 56d on which the DUT 100 is mounted. The DUT mounting portion 56c has a configuration (refer to FIG. 3 and FIG. 7) capable of rotating around a roll axis (a rotation axis in a horizontal direction).

[0037] As shown in FIG. 3, the drive unit 56e includes, for example, a drive motor 56f that rotationally drives the azimuth axis, and a drive motor 56g that rotationally drives the roll axis. The drive unit 56e includes a biaxial positioner provided with a mechanism for performing rotations around the azimuth axis and the roll axis, respectively, by the drive motor 56f and the drive motor 56g. In this way, the drive unit 56e can rotate the DUT 100 mounted on the mounting tray 56d in biaxial (the azimuth axis and the roll axis) directions for each mounting tray 56d. Hereinafter, there is a case where the entire DUT scanning mechanism 56 including the drive unit 56e is referred to as the biaxial positioner (refer to FIG. 3).

[0038] The DUT scanning mechanism (biaxial positioner) 56 performs total spherical scanning which sequentially changes a posture of the DUT 100 in a state in which the antenna 110 faces all orientations (a plurality of preset

orientations) of a surface of the sphere while assuming that the DUT 100 mounted (held) on the mounting tray 56d is disposed, for example, at a center O1 of a sphere (refer to a sphere B in FIGS. 5A and 5B). Control of the DUT scanning in the DUT scanning mechanism 56 is performed by a DUT scanning control unit 16 which will be described later. The DUT scanning mechanism 56 constitutes the positioner in the present invention.

[0039] The test antenna 5 is attached to a required position on the bottom surface 52a of the housing main body 52 of the OTA chamber 50 by using an appropriate holder (not shown). An attachment position of the test antenna 5 is a position at which visibility can be secured from the reflector 7 via an opening 67a provided on the bottom surface 52a. The test antenna 5 uses a radio signal in the frequency band of the same regulation (NR standard) as the antenna 110 of the DUT 100.

[0040] In a case where measurement related to the NR of the DUT 100 is performed in the OTA chamber 50, the test antenna 5 transmits a test signal from the NR system simulator 20 to the DUT 100 and receives a signal under measurement transmitted from the DUT 100 that has received the test signal. The test antenna 5 is disposed so that a light reception surface thereof becomes a focal position F of the reflector 7. The reflector 7 is not always required in a case where the test antenna 5 can be disposed so that the light reception surface thereof faces the DUT 100 and appropriate light reception can be performed.

[0041] The reflector 7 is attached to a required position on the side surface 52b of the OTA chamber 50 by using a reflector holder 58. The reflector 7 realizes a radio wave path that returns the radio signal (the test signal and the signal under measurement) transmitted and received by the antenna 110 of the DUT 100 to the light reception surface of the test antenna 5.

[0042] Subsequently, configurations of the integrated control device 10 and the NR system simulator 20 will be described.

[0043] As shown in FIG. 2, the integrated control device 10 is communicably connected to the NR system simulator 20 via a network 19 such as Ethernet (registered trademark). Further, the integrated control device 10 is also connected to a controlled system element in the OTA chamber 50, for example, the DUT scanning control unit 16 via the network 19.

[0044] The integrated control device 10 comprehensively controls the NR system simulator 20 and the DUT scanning control unit 16 via the network 19, and includes, for example, a Personal Computer (PC). The DUT scanning control unit 16 may be independently provided accompanying with the OTA chamber 50 (refer to FIG. 2), or may be provided in the integrated control device 10 as shown in FIG. 3. Hereinafter, description will be performed while assuming that the integrated control device 10 has the configuration shown in FIG. 3.

[0045] As shown in FIG. 3, the integrated control device 10 includes a control unit 11, an operation unit 12, and a display unit 13. The control unit 11 includes, for example, a computer device. The computer device includes a Central Processing Unit (CPU) 11a that performs predetermined information processing to realize the function of the measurement device 1, and performs comprehensive control on the NR system simulator 20, and the DUT scanning control unit 16 as targets, a Read Only Memory (ROM) 11b that

stores an Operating System (OS) for starting up the CPU 11a, the other programs, and control parameters, and the like, a Random Access Memory (RAM) 11c that stores execution code, data, and the like of the OS or an application which is used for an operation by the CPU 11a, an external I/F unit 11d, an input and output port (not shown), and the like.

[0046] The external I/F unit 11d is communicably connected to each of the NR system simulator 20 and the drive unit 56e of the DUT scanning mechanism (biaxial positioner) 56 via the network 19. An operation unit 12 and a display unit 13 are connected to the input and output port. The operation unit 12 is a functional unit for inputting various information such as commands, and the display unit 13 is a functional unit for displaying various information such as an input screen, measurement results, and the like of the various information.

[0047] The computer device described above functions as the control unit 11 in such a way that the CPU 11a executes a program stored in the ROM 11b while using the RAM 11c as a work area. As shown in FIG. 3, the control unit 11 includes a call connection control unit 14, a signal transmission and reception control unit 15, a DUT scanning control unit 16, a signal analysis control unit 17, a setting control unit 18a, and a rotation speed management control unit 18b. The call connection control unit 14, the signal transmission and reception control unit 15, the DUT scanning control unit 16, the signal analysis control unit 17, the setting control unit 18a, and the rotation speed management control unit 18b are also realized by executing a predetermined program stored in the ROM 11b in the work area of the RAM 11c by the CPU 11a.

[0048] The call connection control unit 14 drives the test antenna 5 via the NR system simulator 20 and the signal processing unit 23 to transmit and receive a control signal (radio signal) to and from the DUT 100, thereby performing control to establish a call (a state where the radio signal can be transmitted and received) between the NR system simulator 20 and the DUT 100.

[0049] The signal transmission and reception control unit 15 performs a control of monitoring a user operation in the operation unit 12, transmitting a signal transmission command to the NR system simulator 20 after the call is established through call connection control, by being triggered with a predetermined measurement start operation related to the measurement of transmission and reception characteristics of the DUT 100 by the user, and transmitting the test signal from the NR system simulator 20 via the test antenna 5, and a control of transmitting a signal reception command and receiving the signal under measurement via the test antenna 5.

[0050] The DUT scanning control unit 16 drives and controls the drive motors 56f and 56g of the DUT scanning mechanism 56 to perform total spherical scanning of the DUT 100 mounted on the mounting tray 56d of the DUT mounting portion 56c.

[0051] Here, the total spherical scanning of the DUT 100 will be described with reference to FIGS. 5A and 5B to FIG. 7. Generally, related to power measurement of a signal radiated by the DUT 100 (radiated power measurement), a method for measuring an Equivalent Isotropic Radiated Power (EIRP) and a method for measuring Total Radiated Power (TRP) are known. The EIRP is, for example, a power value measured at each measurement point (θ , φ) in a

spherical coordinate system (r , θ , φ) shown in FIG. 5A. On the other hand, the TRP is obtained by measuring the EIRP in all orientations of the spherical coordinate system (r , θ , φ), that is, at a plurality of angular sample points PS (refer to FIG. 5B), which are regulated in advance, on a spherical surface equidistant from a center O1 (hereinafter, a reference point) of the total spherical scanning of the DUT 100, and obtaining a total sum thereof.

[0052] In addition, regarding the reception sensitivity measurement, it is known to measure Equivalent Isotropic Sensitivity (EIS). The EIS is, for example, a reception sensitivity value measured at each measurement point (θ , φ) in a spherical coordinate system (r , θ , φ) shown in FIG. 5A.

[0053] The total spherical scanning of the DUT 100 means a control operation of sequentially changing the DUT 100 mounted on the mounting tray 56d in all orientations of a surface of a sphere B while using, for example, a center O1 of the sphere B (refer to FIGS. 5A and 5B) as a reference (center), that is, sequentially changing a posture of the DUT 100 in a state in which the antenna 110 faces the angular sample point PS.

[0054] In order to measure the EIRP or EIS at each angular sample point PS in accordance with the total spherical scanning of the DUT 100, as shown in FIG. 6, the test antenna 5 for receiving a signal radiated by the DUT 100 is disposed at a position of a specific angular sample point PS (one point) in the spherical coordinate system (r , θ , φ), as shown in FIG. 6.

[0055] In the total spherical scanning, the DUT 100 is driven (scanned) so that the antenna surface of the antenna 110 sequentially faces the light reception surface of the test antenna 5. As a result, the test antenna 5 can transmit and receive a signal for the TRP measurement to and from the antenna 110 of the DUT 100 on which the total spherical scanning is performed. Here, the transmitted and received signal is a test signal that is transmitted from the NR system simulator 20 via the test antenna 5, and a signal that is transmitted by the DUT 100, which has received the test signal, using the antenna 110, that is, a signal under measurement that is received via the test antenna 5.

[0056] The total spherical scanning of the DUT 100 is realized by rotationally driving the azimuth axis and the roll axis by the drive motors 56f and 56g which constitutes the DUT scanning mechanism 56. FIG. 7 shows a rotation drive image around the azimuth axis and the roll axis of the DUT scanning mechanism (biaxial positioner) 56 related to the total spherical scanning of the DUT 100 in the measurement device 1. As shown in FIG. 7, the DUT scanning mechanism 56 of the measurement device 1 according to the present embodiment moves the DUT 100 in an angular direction of φ around the azimuth axis, for example, within a range of 180 degrees and moves the DUT 100 in an angular direction of θ around the roll axis, for example, within a range of 360 degrees, so that it is possible to perform the total spherical scanning (refer to FIGS. 5A and 5B and 6) in which the DUT 100 is rotated in all orientations based on the center O1 thereof.

[0057] In FIG. 7, φ_0 indicates a unit movement angle in a total movement angle (180 degrees) in the rotation direction (angular direction of φ) of the azimuth axis, and θ_0 indicates the unit movement angle (hereinafter, step angle) in the total movement angle (360 degrees) in the rotation direction (angular direction of θ) of the roll axis. φ_0 and θ_0 are obtained by enabling, for example, the step angle having a

desired value to be selectively set from a plurality of step angles having different values which are regulated in advance. The set φ_0 and θ_0 regulate an angle between the adjacent angular sample points PS shown in FIG. 5B, and, as a result, regulates the angular sample point PS, that is, the number of measurement positions.

[0058] In order to realize control of the total spherical scanning of the DUT 100 by the DUT scanning control unit 16, for example, a DUT scanning control table 16a is prepared in the ROM 11b in advance. The DUT scanning control table 16a stores, for example, coordinates of each angular sample point PS (refer to FIG. 5B) in the spherical coordinate system (refer to FIG. 5A) related to the total spherical scanning of the DUT 100, drive data of the drive motors 56f and 56g associated with the coordinates of each angular sample point PS, and control data associated with a stop time (measurement time) at each angular sample point PS. In a case where the drive motors 56f and 56g are, for example, stepping motors, for example, the number of drive pulses is stored as the drive data.

[0059] The ROM 11b is further prepared with a rotation speed management table 16b for managing rotation speeds of the drive motor 56f and the drive motor 56g of the DUT scanning mechanism 56. The rotation speed management table 16b manages the rotation speed of the drive motor 56g that rotationally drives the roll axis, and, more specifically, the rotation speed of the drive motor 56g in a case where the DUT scanning mechanism 56 is rotationally driven for each step angle.

[0060] Here, in a case where description is performed with reference to FIGS. 5A and 5B, the step angle indicates an angle between adjacent angular sample points PS (refer to FIG. 5B) in the spherical coordinate system (refer to FIG. 5A) related to the total spherical scanning. The angular sample point PS corresponds to the measurement position of the DUT 100, and the number thereof can be appropriately set to be variable according to a measurement item, a measurement condition, and the like. That is, the unit step angle is obtained by regulating an angle between adjacent measurement positions and may be variable according to the measurement item, the measurement condition, and the like. For the DUT scanning mechanism 56 according to the present embodiment, it is possible to selectively set, for example, a value of 1 degree (deg), 3 degrees, 5 degrees, 7.5 degrees, 10 degrees, 15 degrees, 30 degrees, and 90 degrees for the step angle θ (refer to FIG. 7) of the roll axis by the drive motor 56g.

[0061] The present embodiment is not limited thereto, instead of the rotation speed management table 16b (first rotation speed management table), a second rotation speed management table may be provided which manages a rotation speed of the drive motor 56f, which can minimize the movement time of the DUT scanning mechanism 56 in each step section to correspond to each step angle (corresponding to φ in FIG. 7) of the azimuth axis, for example, 5 degrees, 10 degrees, 15 degrees, or 30 degrees.

[0062] Further, instead of the first rotation speed management table and the second rotation speed management table, a third rotation speed management table may be provided which manages the rotation speed of the drive motor 56g and the drive motor 56f, which can minimize the movement time of the DUT scanning mechanism 56 in each step section to correspond to each step angle θ of the roll axis and each step angle φ of the azimuth axis.

[0063] The DUT scanning control unit 16 expands the DUT scanning control table 16a into the work area of the RAM 11c, and drives and controls the drive motors 56f and 56g of the DUT scanning mechanism 56 based on the control data stored in the DUT scanning control table 16a. As a result, the total spherical scanning of the DUT 100 mounted on the DUT mounting portion 56c is performed. In the total spherical scanning, the antenna surface of the antenna 110 of the DUT 100 is stopped for a regulated time (the stop time) toward the angular sample point PS for each angular sample point PS in the spherical coordinate system, and, thereafter, an operation of moving to a next angular sample point PS (scanning of the DUT 100) is sequentially performed while targeting all the angular sample points PS.

[0064] Further, the DUT scanning control unit 16 performs rotation speed control on the drive motor 56g related to the movement of the DUT scanning mechanism 56 targeting each step angle θ of the roll axis using the rotation speed management table 16b under the control of the rotation speed management control unit 18b, which will be described later, in accordance with the total spherical scanning of the DUT scanning mechanism 56 using the DUT scanning control table 16a.

[0065] The signal analysis control unit 17 captures a radio signal, which is related to the NR and is received by the test antenna 5 in a case where the total spherical scanning of the DUT 100 is performed, via the NR system simulator 20, and performs an analysis process (measurement process) on the radio signal as a signal of a specific measurement item.

[0066] The setting control unit 18a is a functional unit for setting various information necessary to execute the rotation speed control of the drive motor 56f using the rotation speed management table 16b by the DUT scanning control unit 16. In a case where the specific measurement item is measured, the setting control unit 18a can selectively set a step angle of a desired value from among step angles (θ , φ) having a plurality of different values, for example, 5 degrees, 10 degrees, 15 degrees, and 30 degrees.

[0067] For example, the rotation speed management control unit 18b performs the rotation speed control of the drive motor 56f related to the movement of the DUT scanning mechanism 56 targeting each step angle θ of the roll axis in cooperation with the DUT scanning control unit 16 using the rotation speed management table 16b in accordance with the total spherical scanning of the DUT scanning mechanism 56 in a case where the TRP measurement is performed.

[0068] As shown in FIG. 4, the NR system simulator 20 includes a signal generation unit 21a, a signal measurement unit 21b, a transmission and reception unit 21c, a control unit 21d, an operation unit 21e, and a display unit 21f. The NR system simulator 20 constitutes a simulated measurement device of the present invention.

[0069] The signal generation unit 21a generates a signal (baseband signal) that becomes a source of the test signal. The transmission and reception unit 21c functions as an RF unit that generates the test signal corresponding to a frequency of each communication standard from the signal generated by the signal generation unit 21a and sends the generated test signal to the signal processing unit 23, and restores the baseband signal from the signal under measurement which is sent from the signal processing unit 23. The signal measurement unit 21b performs a measurement process of the signal under measurement based on the baseband signal restored by the transmission and reception unit 21c.

[0070] The control unit 21d comprehensively controls each of the functional units including the signal generation unit 21a, the signal measurement unit 21b, the transmission and reception unit 21c, the operation unit 21e, and the display unit 21f. The operation unit 21e is a functional unit for inputting various information such as commands, and the display unit 21f is a functional unit for displaying various information such as an input screen and measurement results of the various information.

[0071] In the measurement device 1 having the above-described configuration, the DUT 100 is mounted on the mounting tray 56d of the DUT scanning mechanism (biaxial positioner) 56 in the internal space 51 of the OTA chamber 50. Therefore, it is possible to perform measurement of the specific measurement item, such as measurement of the EIRP at each measurement position and measurement of the TRP over all measurement positions, while moving (rotating) the DUT 100 by a preset step angle in the biaxial (azimuth axis and roll axis) direction for each mounting tray 56d.

[0072] In such a measurement device 1, in a case where the measurement is performed at each angular sample point PS, it was found that the behavior of the DUT 100, such as the antenna control, changes, resulting in different measurement results depending on the operation path of the DUT scanning mechanism 56 to the measurement position.

[0073] As shown in FIG. 8, in a case where the measurement of the measurement position indicated by the white point among the angular sample points PS defined by the rotation angle θ of the roll axis and the rotation angle φ of the azimuth axis indicated by the black points is performed, for example, the value of the EIRP measured in a case where the DUT scanning mechanism 56 is operated along a path indicated by the arrow A in FIG. 8 is different from the value of the EIRP measured in a case where the DUT scanning mechanism 56 is operated along a path indicated by the arrow B in FIG. 8.

[0074] The values in the left column of “EIRP result (dBm)” of the table on the right side of FIG. 8 are values in a case where the DUT scanning mechanism 56 is operated along a path indicated by the arrow A in FIG. 8, and the values in the right column are values in a case where the DUT scanning mechanism 56 is operated along a path indicated by the arrow B in FIG. 8, and show the results of the five measurements.

[0075] Since the difference in the measurement results at the same measurement position is suppressed to improve the measurement reproducibility, the DUT scanning control unit 16 of the present embodiment stores the operation path of the DUT scanning mechanism 56 to the measurement position, and when performing the next measurement, reproduces the path to reach the measurement position.

[0076] Therefore, the DUT scanning control unit 16 includes a positioner operation recording unit 16c and a positioner operation control unit 16d.

[0077] The positioner operation recording unit 16c stores the operation path of the DUT scanning mechanism 56 to the measurement position by tracing back from the measurement position to a preset number of angular sample points PS. In addition, the positioner operation recording unit 16c stores different operation paths up to a preset number in a case where the operation path of the DUT scanning mechanism 56 to the measurement position is an operation path different from the stored operation path. The positioner

operation recording unit 16c stores the operation path of the DUT scanning mechanism 56 by, for example, storing the angle changes made by the DUT scanning mechanism 56. The positioner operation recording unit 16c may store measurement information such as the measurement results in association with the operation path.

[0078] When reproduction of an operation path is selected by the operation input of the user to the operation unit 12 and an operation path to be reproduced is selected from the operation paths stored in the positioner operation recording unit 16c, the positioner operation control unit 16d controls the DUT scanning mechanism 56 to adjust the DUT 100 to the angle of the measurement position by the selected operation path.

[0079] For example, in a case where the measurement is advanced along a path of the angular sample points PS indicated by solid line arrows as shown on the left side of FIG. 9, the positioner operation recording unit 16c stores the operation path. Then, in a case where the reproduction of the operation path is selected when performing measurement at the measurement position indicated by the white point shown on the right side of FIG. 9, the positioner operation control unit 16d controls the DUT scanning mechanism 56 to change the angle of the DUT 100 to the measurement position along a path indicated by dotted line arrows.

[0080] As described above, the above-described embodiment includes a positioner operation recording unit 16c that stores an operation path of the DUT scanning mechanism 56 to the measurement position by tracing back from the measurement position to a preset number of the angular sample points PS, and a positioner operation control unit 16d that controls the DUT scanning mechanism 56 according to the operation path stored in the positioner operation recording unit 16c to adjust the DUT 100 to an angle of the measurement position when performing measurement at the measurement position.

[0081] As a result, the operation path of the DUT scanning mechanism 56 to the measurement position is stored by tracing back from the measurement position to a preset number of angular sample points PS, and the DUT 100 is adjusted to the angle of the measurement position according to the stored path when performing measurement at the measurement position. Therefore, measurement reproducibility at the same measurement position can be improved.

[0082] In addition, the positioner operation recording unit 16c stores different operation paths up to a preset number in a case where the operation path of the DUT scanning mechanism 56 to the measurement position is an operation path different from the stored operation path.

[0083] Accordingly, in a case where the operation path to the measurement position is an operation path different from the stored operation path, different operation paths are stored up to a preset number. Therefore, measurement reproducibility at the same measurement position can be improved.

[0084] Hitherto, the embodiments of the present invention have been disclosed, but it is clear that changes can be made by those skilled in the art without departing from the scope of the present invention. All such modifications and equivalents are intended to be included in the claims as follows.

DESCRIPTION OF REFERENCE NUMERALS
AND SIGNS

- [0085] 1: Measurement device (mobile terminal testing device)
 [0086] 5: Test antenna
 [0087] 10: Integrated control device
 [0088] 16: DUT scanning control unit
 [0089] 16c: Positioner operation recording unit
 [0090] 16d: Positioner operation control unit
 [0091] 20: NR system simulator (simulated measurement device)
 [0092] 50: OTA chamber (anechoic box)
 [0093] 51: Internal space
 [0094] 56: DUT scanning mechanism (positioner)
 [0095] 56f, 56g: Drive motor
 [0096] 100: DUT (mobile terminal)

What is claimed is:

1. A mobile terminal testing device comprising:
 - a positioner that is provided in an internal space of an anechoic box, has an azimuth axis and a roll axis that are each rotationally drivable by a drive motor, and rotates a mobile terminal that is a device under test so that the mobile terminal sequentially faces a plurality of preset angular sample points of a spherical coordinate system, using a center of the spherical coordinate system as a reference point;
 - a simulated measurement device connected to a test antenna in the internal space;
 - an integrated control device that controls the simulated measurement device so that a measurement operation of transmitting a test signal from the test antenna to the mobile terminal, receiving a signal under measurement transmitted from the mobile terminal that has received the test signal by using the test antenna, and measuring a specific measurement item related to the mobile terminal based on the received signal under measurement is performed at a measurement position corresponding to each of the plurality of angular sample points; and
 - a positioner operation recording unit that stores an operation path of the positioner to the measurement position by tracing back from the measurement position to a preset number of the angular sample points; and
 - a positioner operation control unit that controls the positioner according to the operation path stored in the positioner operation recording unit to adjust the mobile

terminal to an angle of the measurement position when performing measurement at the measurement position.

2. The mobile terminal testing device according to claim 1,

wherein the positioner operation recording unit stores different operation paths up to a preset number in a case where the operation path of the positioner to the measurement position is an operation path different from the stored operation path.

3. A mobile terminal testing method of a mobile terminal testing device including a positioner that is provided in an internal space of an anechoic box, has an azimuth axis and a roll axis that are each rotationally drivable by a drive motor, and rotates a mobile terminal that is a device under test so that the mobile terminal sequentially faces a plurality of preset angular sample points of a spherical coordinate system, using a center of the spherical coordinate system as a reference point, a simulated measurement device connected to a test antenna in the internal space, and an integrated control device that controls the simulated measurement device so that a measurement operation of transmitting a test signal from the test antenna to the mobile terminal, receiving a signal under measurement transmitted from the mobile terminal that has received the test signal by using the test antenna, and measuring a specific measurement item related to the mobile terminal based on the received signal under measurement is performed at a measurement position corresponding to each of the plurality of angular sample points, the mobile terminal testing method comprising:

a step of storing an operation path of the positioner to the measurement position by tracing back from the measurement position to a preset number of the angular sample points; and

a step of controlling the positioner according to the stored operation path to adjust the mobile terminal to an angle of the measurement position when performing measurement at the measurement position.

4. The mobile terminal testing method according to claim 3,

wherein the step of storing the operation path of the positioner is a step of storing different operation paths up to a preset number in a case where the operation path of the positioner to the measurement position is an operation path different from the stored operation path.

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