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## 导引头稳定平台控制回路设计分析 [\(PDF\)](#)

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Title: Analysis on Design of Control Loop for Seeker Stabilized Platform

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关键词: [导引头](#); [隔离度](#); [视线角速度](#); [ITAE II型系统](#)

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摘要: 在稳定平台控制系统中分析了载体扰动产生的干扰力矩及对视线角引起的摆动, 分析了选择不同的视线角速度输出点时对视线角速度、隔离度的影响及对控制系统传函的要求, 为选择电机输出力矩、选择陀螺量程及控制系统传函的设计提供了理论依据。在分析的基础上构建了数字仿真试验系统, 仿真表明视线角速度输出有较好的品质和较高的隔离度。

Abstract: The disturbing torque caused by carrier perturbation in the control system of seeker stabilized platform and the swing caused by sight angular angle were analyzed, the influence of selection of different output dot of sight angular speed on sight angle and decoupling and the requirement for control system transfer function were analyzed. The analyses lay theoretic foundation for motor output torque and gyro range selection and design of control system transfer function. The digital simulation system was built based on the analyses. The digital simulation result shows better decoupling is achieved in sight angular speed

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