AEROSPACE RECOMMENDED PRACTICE

ARP4895™	REV. B
Issued 1994-02 Revised 2019-05 Reaffirmed 2024-12 Superseding ARP4895A	

Flight Control Actuators - Dynamic Seals, Collection of Duty Cycle Data

RATIONALE

This revision clarifies the description of an algorithm introduced in Revision A.

ARP4895B has been reaffirmed to comply with the SAE Five-Year Review policy.

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1. SCOPE

This SAE Aerospace Recommended Practice (ARP) provides an algorithm aimed to analyze flight control surface actuator movements with the objective to generate duty cycle data applicable to hydraulic actuator dynamic seals.

1.1 Purpose

This algorithm can be used to process digitally recorded actuator positions, generated either by pure simulation, or hardware-in-the-loop simulation, or flight test of full scale demonstrator of new aircraft, of new aircraft models in development, or of in-service aircraft, depending on what is available at different stages of the aircraft development and the purpose of the duty cycle investigation. This generated duty cycle data can be used as a basis for defining dynamic seal life requirements, dynamic seal life testing, or to assess the impact of control law or other changes to dynamic seal behavior.

2. APPLICABLE DOCUMENTS

The following publications form a part of this document to the extent specified herein. The latest issue of SAE publications shall apply. The applicable issue of other publications shall be the issue in effect on the date of the purchase order. In the event of conflict between the text of this document and references cited herein, the text of this document takes precedence. Nothing in this document, however, supersedes applicable laws and regulations unless a specific exemption has been obtained.

2.1 SAE Publications

Available from SAE International, 400 Commonwealth Drive, Warrendale, PA15096-0001, Tel: 877-606-7323 (inside USA and Canada) or +1 724-776-4970 (outside USA), www.sae.org.

ARP1281 Actuators: Aircraft Flight Controls, Power Operated, Hydraulic, General Specification For

2.2 Other Publications

Royal Aircraft Establishment Report 69096 - An Investigation into the Duty Cycle of Powered Flying Controls, F. Holombek, May 1969.

3. BACKGROUND

3.1 Past Practice

Actuator displacement duty cycle requirements used in the qualification of past fly-by-wire aircraft have been established analytically from a limited amount of flight test data. Studies analyzing flight test data have been very limited in scope. A Royal Aircraft Establishment study in the late 1960s indicated that the control actuator usage for aircraft with unaugmented mechanical control systems was less "arduous" than the design requirements. No systematic, quantified investigation into the flight control demands has been undertaken for highly augmented or totally fly-by-wire aircraft. A major concern in the development of actuators for this type aircraft is actuator endurance in terms of mechanical wear and particularly seal life.

3.2 Recommended Practice

Displacement duty cycle data should be collected from aircraft that are advanced technology demonstrators and full-scale development programs. The collection of data during the development testing phase of new aircraft is very cost-effective because these aircraft are normally highly instrumented, and all the data are recorded on-board the aircraft and/or in a telemetry ground station.

Normally, several flight control system parameters are monitored on all test aircraft to assure safety of flight. The parameters typically include aircraft rates and accelerations, pilot primary control inputs, and control surface positions.

The duty cycle collection method identified in this ARP makes use of a computer algorithm which can run real time in a telemetry ground station. Data recorded on board the aircraft can be post-flight processed if a real time telemetry ground station is not available.

Limitations for real time data processing are telemetered parameters, data sample rate, and ground station capability. If small reversals are considered important, sample rates and timing of the sampling may be statistically important.

Limitations for post-flight non-real time processing of data are the cost and logistics of replaying hundreds of hours of recorded data.

However, the described algorithm can also be used in other contexts as mentioned in the scope

4. ACTUATOR DISPLACEMENT DATA ACQUISITION

4.1 Digital Data Acquisition

The position data sampling frequency should be selected high enough so as not to lose any information. The theoretical minimum is twice the frequency of the movement to be analyzed. If the movement frequency is not precisely known, it is safe to consider a margin, typically a factor of five or higher (rather than two). The benefits of higher sampling rates should be considered, as even with a sampling ratio five times higher than the oscillation frequency, there is a max error of 4.8% on the peak-to-peak value.

4.2 Data Identification and Collection

In order to manage the collection of actuator displacement data, all of the actuator reversals shall be counted and the displacement amplitudes be lumped in a limited number of levels based on percent of stroke ranges. Because the effects of an augmentation system is a major area of interest, the number of smaller reversals should have better resolution than the larger amplitude reversals. The data should be segregated by flight phase; e.g., ground operation, takeoff/landing configuration, and other regimes through the flight envelope

4.3 Data Analysis

An actuator displacement usage algorithm should operate as shown in Figure 1. The algorithm is based on a consecutive three point approach to determine the existence of a peak or valley. The algorithm identifies a peak when the middle point has a value greater than or equal to the preceding point and has a value greater than the succeeding point. Likewise, a valley is identified when the middle point has a value less than the preceding point and has a value less than or equal to the succeeding point. The stroke can then be determined by calculating the displacement between the peak and the valley.

To eliminate the possibility of identifying incorrect peaks or valleys (for instance, due to data dropouts), the algorithm calculates the actuator rate between successive points. If the calculated rate exceeds the actuator maximum rate capability, the algorithm ignores that data point. Care must be taken when choosing the rate at which the data point is ignored, as during transients the rate can be greater than the maximum specified actuator rate. In practice, speed can be greater under certain transient conditions such as:

- Under aiding load conditions
- During transients, such as those due to oscillations that can occur at certain frequencies due to the hydromechanical coupling of fluid compliance and load inertia

Data processed by the algorithm either in real time or by replay can be stored and sorted into displacement "bins," i.e., 0 to 2%, 2 to 5%, 5 to 10%, 10 to 25%, 25 to 50%, 50 to 75%, 75 to 100%. The data can then be presented in a histogram format. The number of displacement bins in this example was chosen to be similar to the duty cycle recommendation presented in ARP1281. The user of this algorithm can select any number displacement range bins.

A flow chart for the actuator reversal calculation program is presented in Figure 2A.

4.4 Data Sample

An example of flight test data that has been processed by the algorithm is shown in Figures 3 and 4. The data for this example was chosen because parade formation is a non-maneuvering flight phase that requires highly precise pilot inputs and results in a larger number for small actuator displacements.

The symbols shown on the plots in Figure 3 shows points which are picked by the algorithm without a minimum displacement window. Figure 4 shows the results of incorporating a 0.25% (0.09 degree) minimum displacement window. The minimum displacement window is a user defined parameter which can be set at any value to prevent the algorithm from processing noise in the instrumentation system. It may be based on the knowledge of the quality of the acquisition chain, in terms of noise or resolution, or actual actuator position servo loop performance.

It shall not be ignored that actual position threshold may be lower than specified. The 0.25% minimum displacement was chosen for the example because it corresponds to the actuator threshold. Histograms of the data from Figures 3 and 4 are presented in Figure 5.

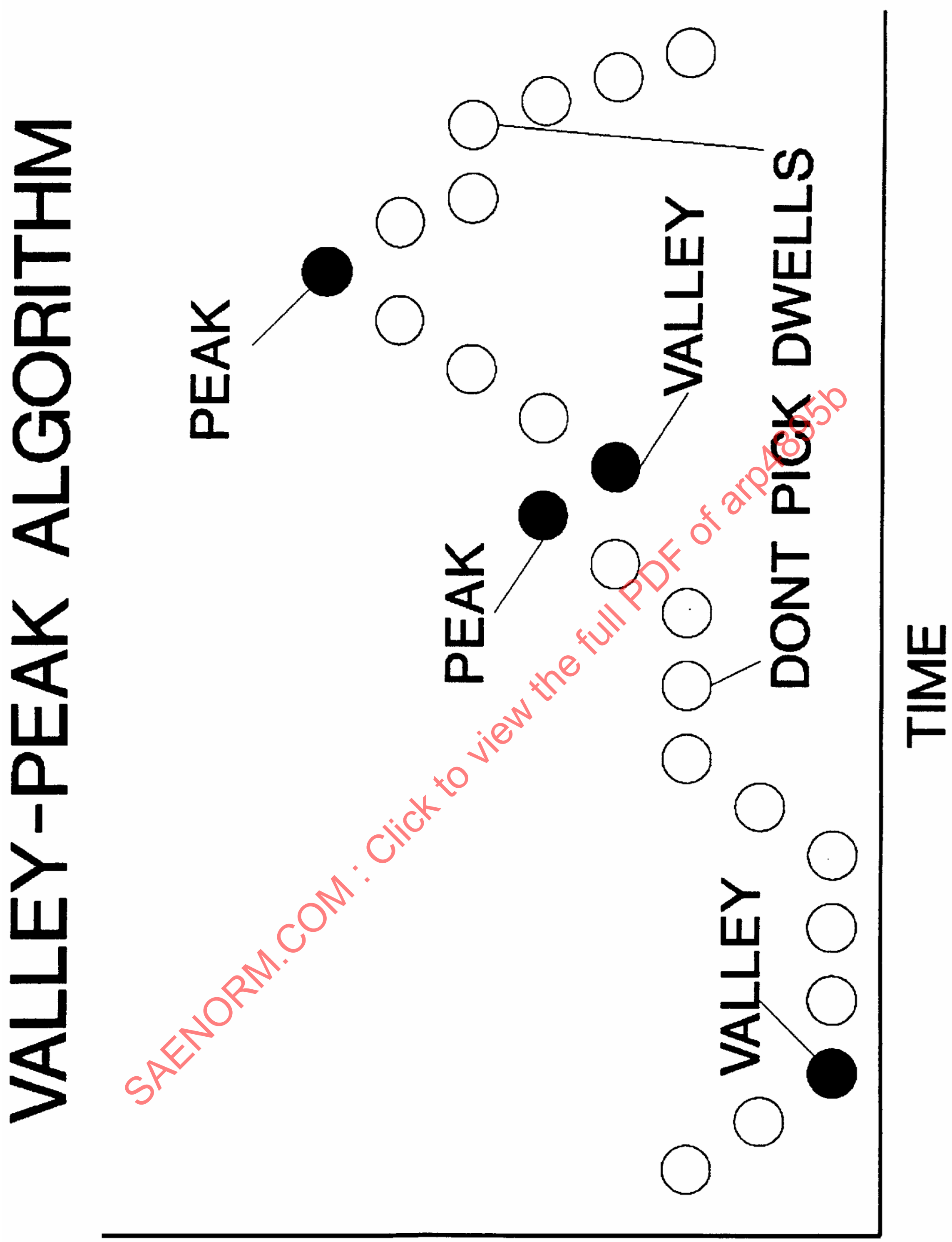


Figure 1 - Valley-peak algorithm

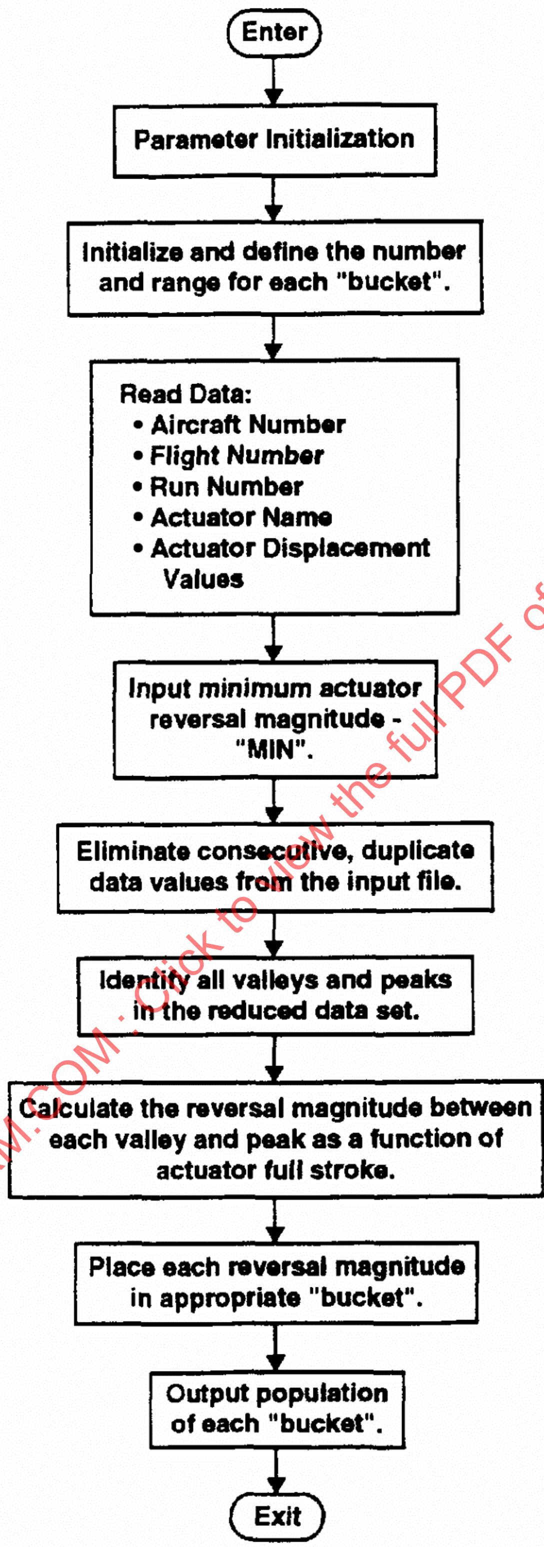
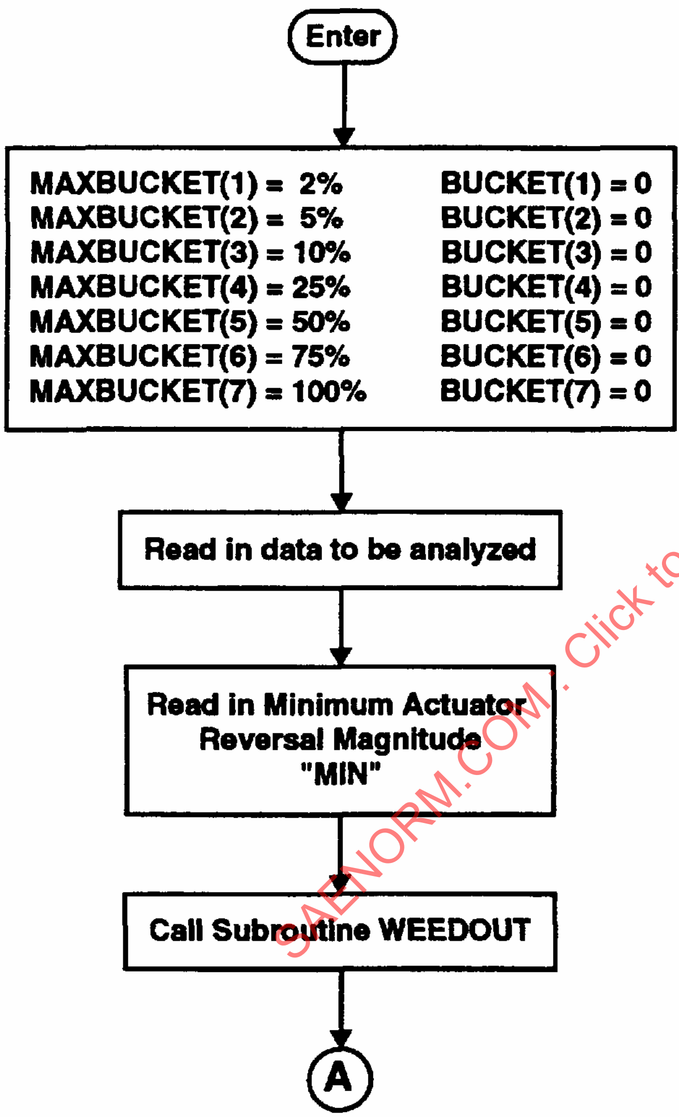


Figure 2A - Actuator reversal calculation program

Initialization



Seven distinct "buckets" are defined with each "bucket" representing a percentage range for full actuator stroke. This range is defined by MAXBUCKET. There is also a counter called BUCKET which tallies the number of reversal magnitudes that fall into each respective "bucket" range.

Data can be from aircraft flight test, ground test, or laboratory testing. Data may consist of aircraft number, flight number, run number, test number, name of actuator being analyzed, and actuator displacement values.

Defines the minimum actuator stroke to be used in determining if a peak or a valley has occurred.

Eliminates all consecutive, duplicate data values from the input file.

Figure 2B - Actuator reversal calculation program

Subroutine WEEDOUT

Purpose: Eliminates duplicate data values. Reduces processing time required when looking for a peak or a valley.

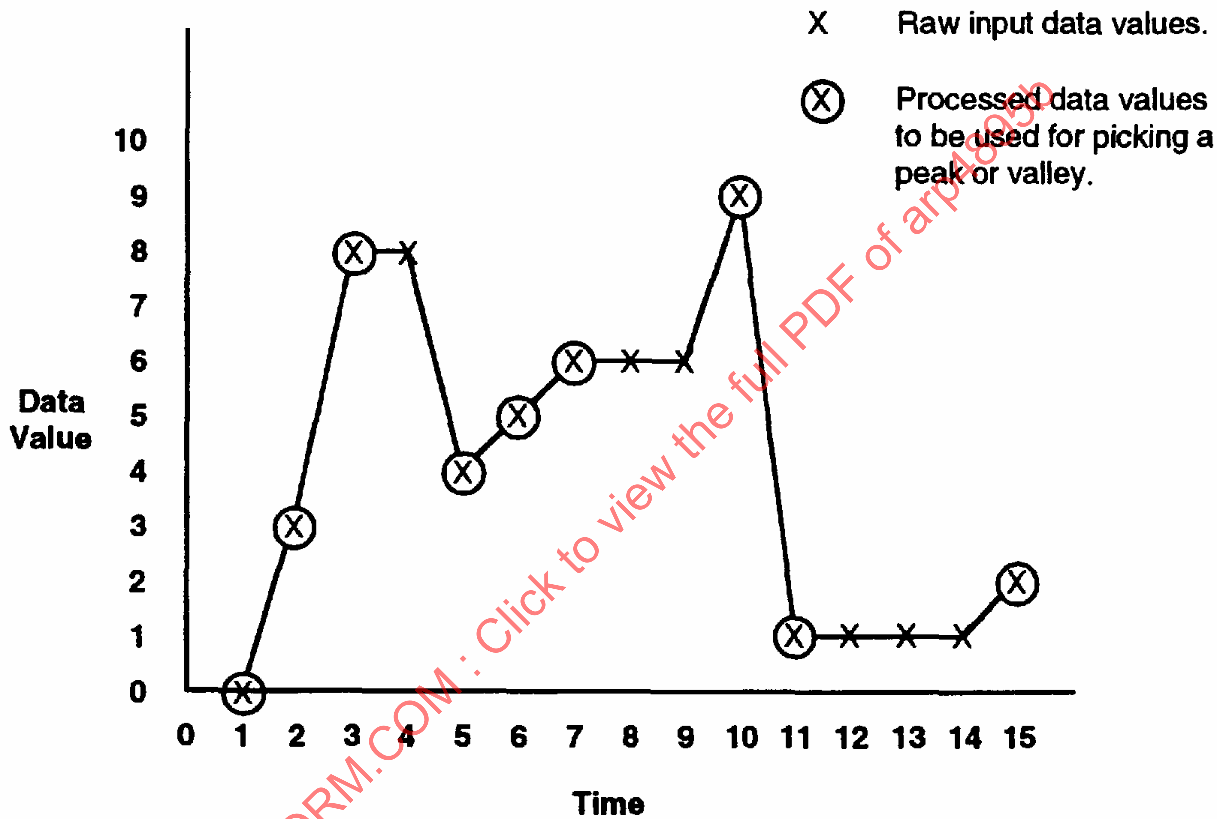


Figure 2C - Actuator reversal calculation program

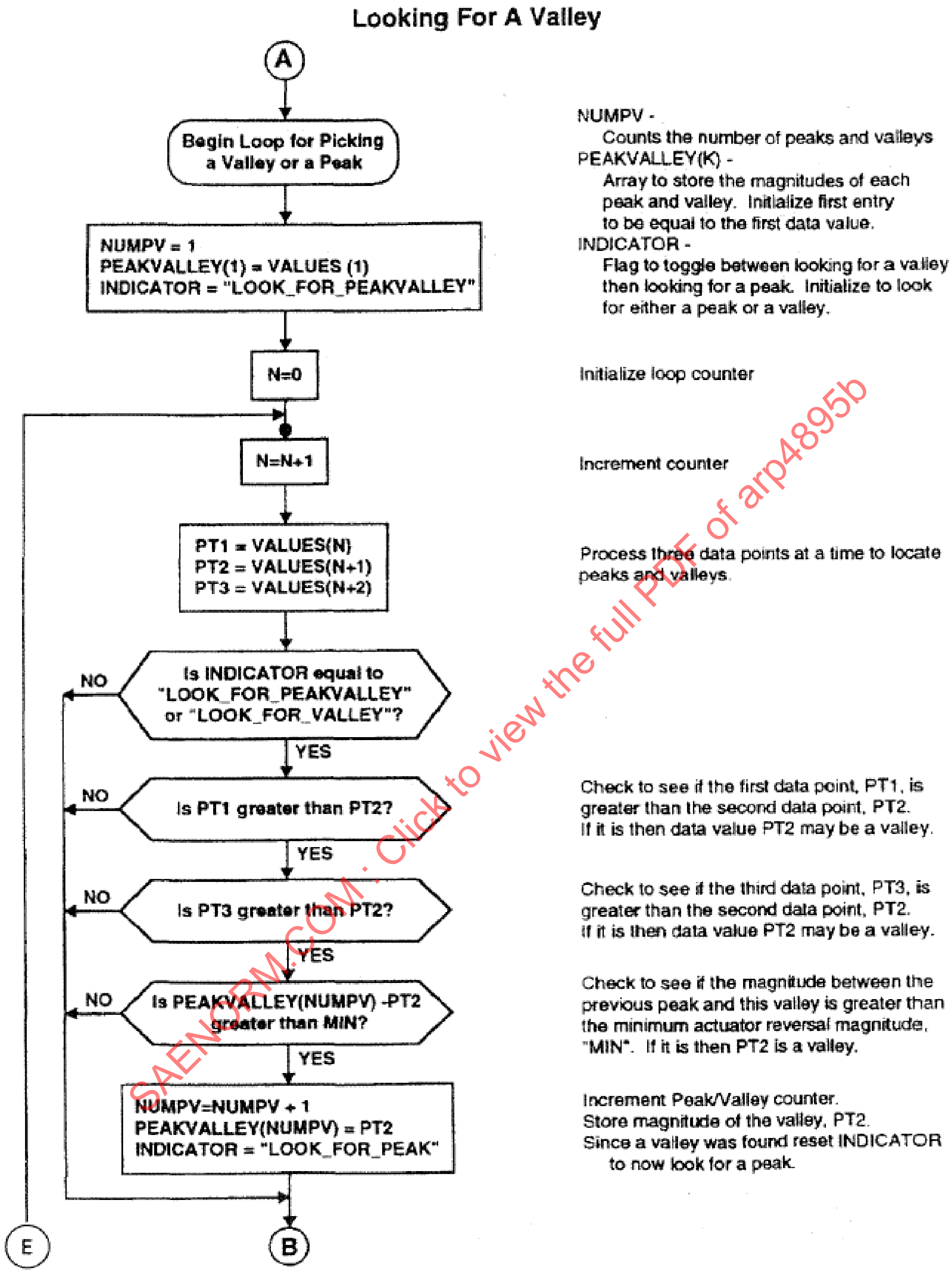
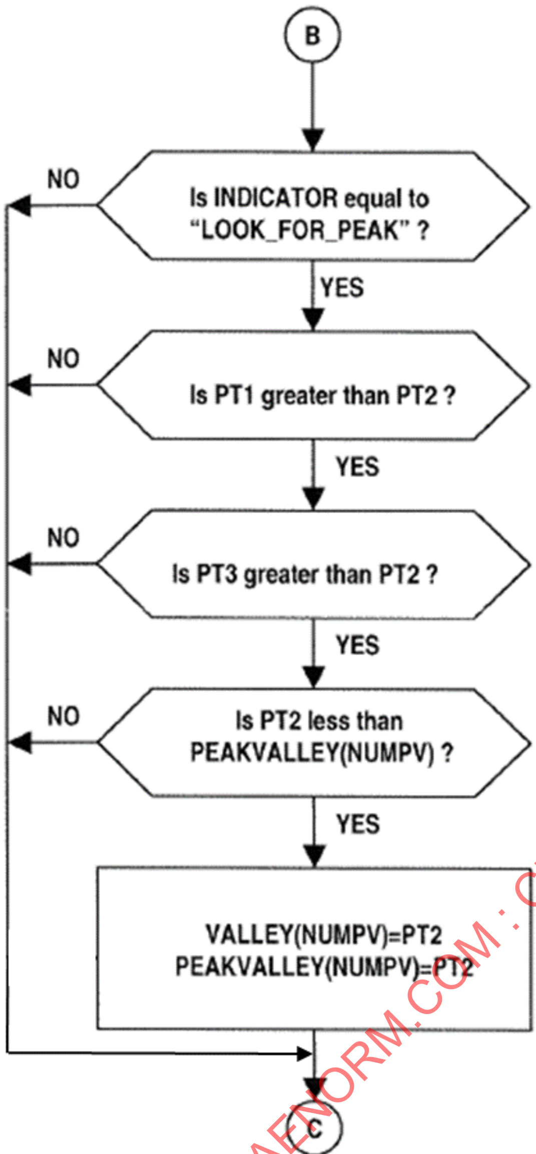


Figure 2D - Actuator reversal calculation program

Looking For A Peak, But Found A Valley



Check to see if the first data point, PT1 is greater than the second data point PT2. If it is, then data value PT2 may be a valley.

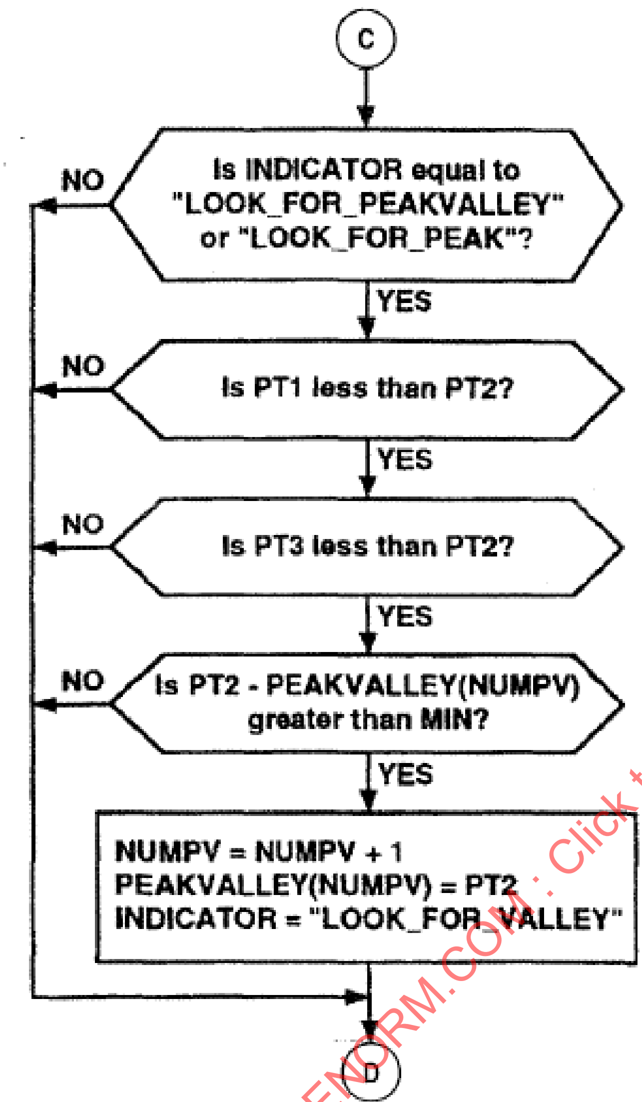
Check to see if the third data point, PT3 is greater than the second data point PT2. If it is, then data value PT2 may be a valley.

Check to see if the second data point, PT2 is less than the last valley.

Replace the value of the last valley with the value PT2

Figure 2E - Actuator reversal calculation program

Looking For A Peak



Check to see if the first data point, PT1, is less than the second data point, PT2.
If it is then data value PT2 may be a peak.

Check to see if the third data point, PT3, is less than the second data point, PT2.
If it is then data value PT2 may be a peak.

Check to see if the magnitude between the previous valley and this peak is greater than the minimum actuator reversal magnitude, "MIN". If it is then PT2 is a peak.

Increment Peak/Valley counter.
Store magnitude of the peak, PT2.
Since a peak was found reset INDICATOR to now look for a valley.

Figure 2F - Actuator reversal calculation program

Looking For A Valley, But Found A Peak

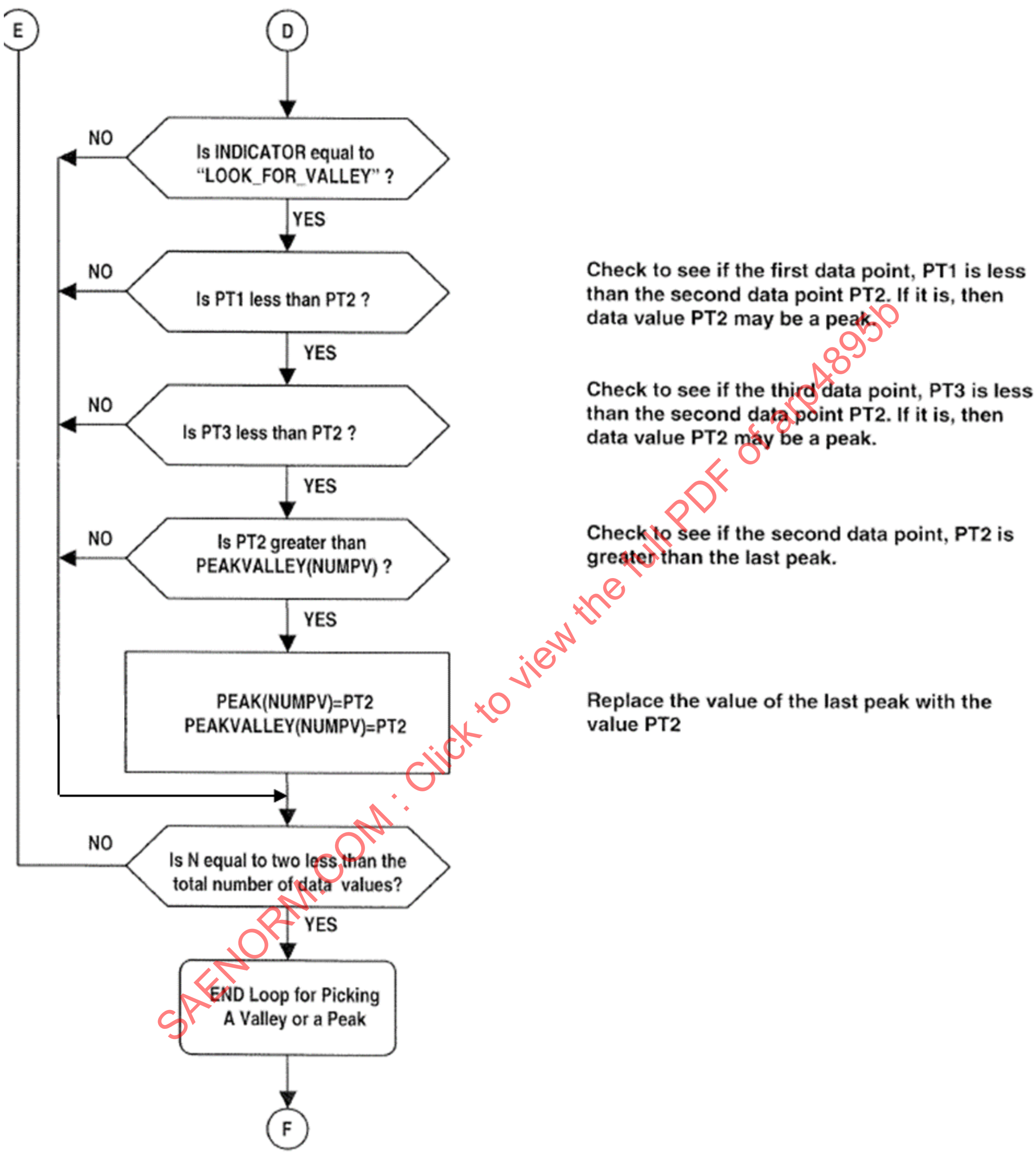


Figure 2G - Actuator reversal calculation program

Actuator Reversal Magnitude Calculation

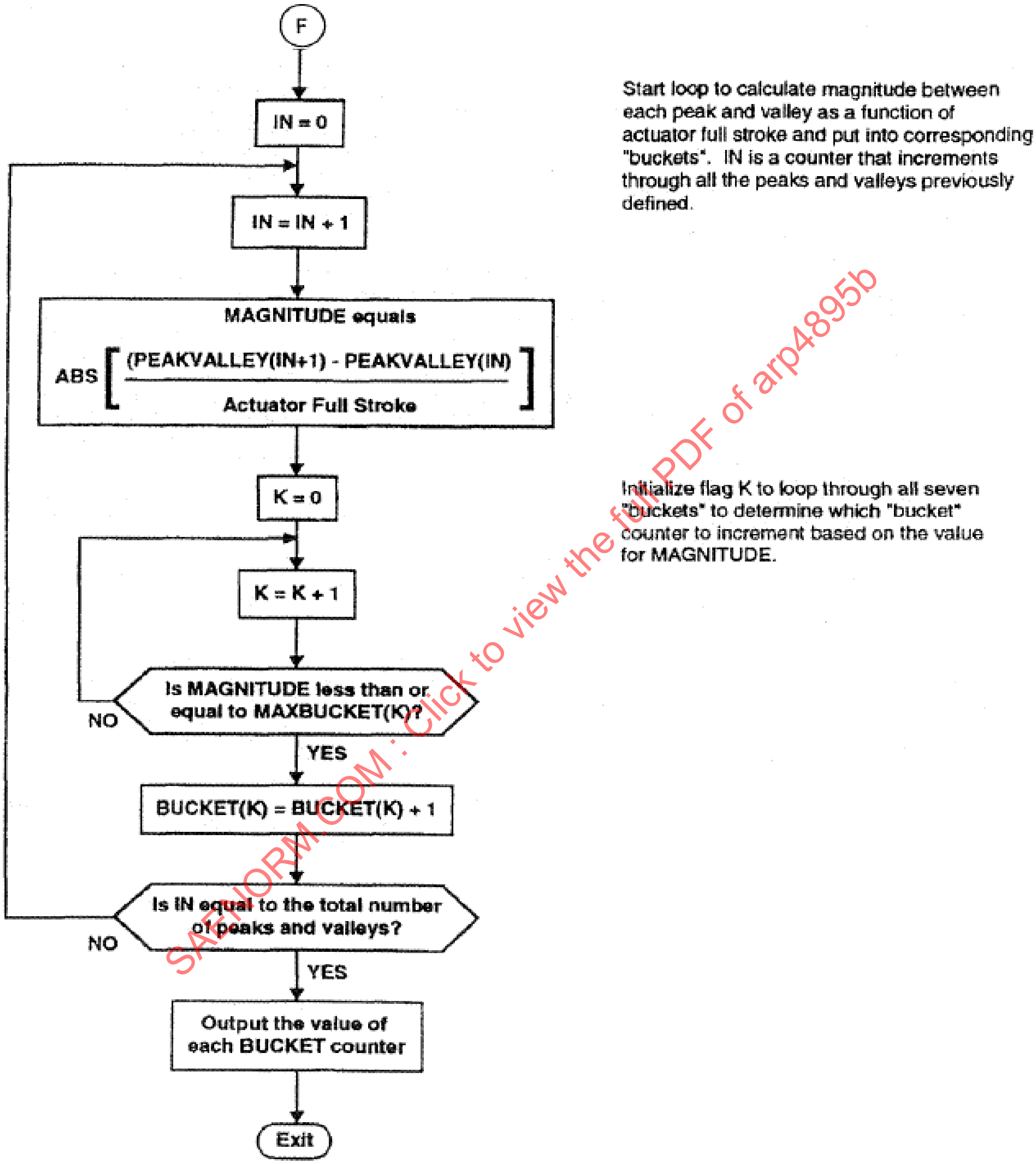
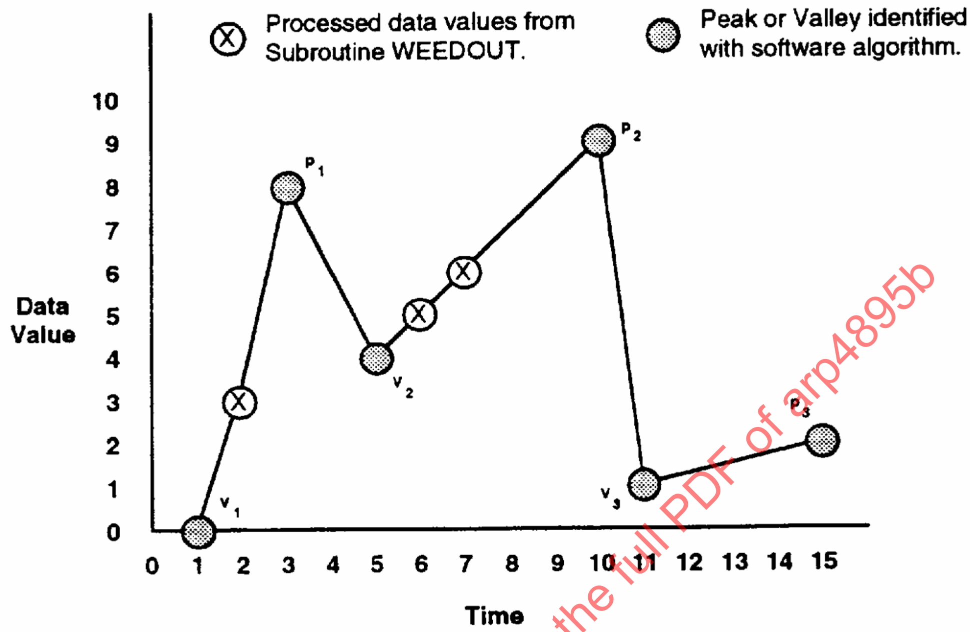


Figure 2H - Actuator reversal calculation program

Program Outputs

Peak and Valley Identification



Actuator Reversal Tabulation

	Delta Actuator Stroke (Percent) *
$V_1 \rightarrow P_1$	80%
$P_1 \rightarrow V_2$	40%
$V_2 \rightarrow P_2$	50%
$P_2 \rightarrow V_3$	80%
$V_3 \rightarrow P_3$	10%

Actuator Reversals	
Bucket	Counts
0 - 2%	0
2 - 5%	0
5 - 10%	1
10 - 25%	0
25 - 50%	1
50 - 75%	1
75 - 100%	2

* Assumes a value of 10 for maximum actuator stroke.

Figure 2I - Actuator reversal calculation program