

CATEGORY 7-NAVIGATION AND AVIONICS

7A SYSTEMS, EQUIPMENT AND COMPONENTS

N.B.:

For automatic pilots for underwater vehicles, see Category 8.

For radar, see Category 6. (L.N. 65 of 2004)

7A001 Accelerometers as follows and specially designed components for accelerometers:

N.B.:

For angular or rotational accelerometers, see 7A001(b). See also 7A101.

- (a) Linear accelerometers having any of the following characteristics:
 - (1) Specified to function at linear acceleration levels less than or equal to 15 g and having:
 - (a) A "bias" "stability" of less (better) than 130 micro g with respect to a fixed calibration value over a period of one year; *or*
 - (b) A "scale factor" "stability" of less (better) than 130 ppm with respect to a fixed calibration value over a period of one year;
 - (2) Specified to function at linear acceleration levels exceeding 15 g and having:
 - (a) A "bias" "repeatability" of less (better) than 5000 micro g over a period of one year; *and*
 - (b) A "scale factor" "repeatability" of less (better) than 2500 ppm over a period of one year;
 - (3) Designed for use in inertial navigation or guidance systems and specified to function at linear acceleration levels exceeding 100 g; *and*
- (b) Angular or rotational accelerometers, specified to function at linear acceleration levels exceeding 100 g;

(L.N. 254 of 2008)

7A002 Gyros or angular rate sensors, having any of the following characteristics and specially designed components for gyros or angular rate sensors:

N.B.:

See also 7A102. For angular or rotational accelerometers, see 7A001(b).

- (a) A "bias" "stability", when measured in a 1 g environment over a period of one month, and with respect to a fixed calibration value of less (better) than 0.5 degree per hour when specified to function at linear acceleration levels up to and including 100 g;
- (b) An "angle random walk" of less (better) than or equal to 0.0035 degree per square root hour;

Note:

7A002(b) does not include 'spinning mass gyros'.

Technical Note:

'Spinning mass gyros' are gyros which use a continually rotating mass to sense angular motion.

- (c) A rate range greater than or equal to 500 degrees per second and having:
 - (1) A "bias" "stability", when measured in a 1 g environment over a period of three minutes, and with respect to a fixed calibration value of less (better) than 40 degrees per hour; *or*
 - (2) An "angle random walk" of less (better) than or equal to 0.2 degree per square root hour;
- (d) Specified to function at linear acceleration levels exceeding 100 g;

7A003 Inertial systems and specially designed components, as follows:

N.B.:

See also 7A103.

- (a) Inertial Navigation Systems (INS) (gimballed or strapdown) and inertial equipment, designed for "aircraft", land vehicles, vessels (surface or underwater) or "spacecraft", for navigation, attitude, guidance or control and having any of the following characteristics and specially designed components for those INS and inertial equipment:
 - (1) Navigation error (free inertial) subsequent to normal alignment of 0.8 nautical mile per hour (nm/h) 'Circular Error Probable' ('CEP') or less (better);
 - (2) Specified to function at linear acceleration levels exceeding 10 g;
- (b) Hybrid Inertial Navigation Systems embedded with Global Navigation Satellite System(s) (GNSS) or with "Data-Based Referenced Navigation" ("DBRN") System(s) for navigation, attitude, guidance or control, subsequent to normal alignment and having an INS navigation position accuracy, after loss of GNSS or "DBRN" for a period of up to 4 minutes, of less (better) than 10 metres 'CEP';
- (c) Inertial Measurement equipment for heading or True North determination and having any of the following characteristics and specially designed components for those Inertial Measurement equipment: (L.N. 226 of 2009)
 - (1) Designed to have heading or True North determination accuracy equal to or less (better) than 0.07 deg sec(Lat) (equivalent to 6 arc minutes rms at 45 degrees latitude); (L.N. 226 of 2009)
 - (2) Designed to have a non-operating shock level of 900 g or greater at a duration of 1 msec or greater; *and*
- (d) Inertial Measurement equipment including Inertial Measurement Units (IMU) and Inertial Reference Systems (IRS), incorporating accelerometers or gyros specified in 7A001 or 7A002, and specially designed components for those Inertial Measurement equipment;

Notes:

- 1. The parameters of 7A003(a) and 7A003(b) are applicable with any of the following environmental conditions:
 - (a) Input random vibration with an overall magnitude of 7.7 g rms in the first 0.5 hour and a total test duration of 1.5 hours per axis in each of the 3 perpendicular axes, when the random vibration meets all of the following:
 - (1) A constant power spectral density (PSD) value of 0.04 g²/Hz over a frequency interval of 15 to 1000 Hz;
 - (2) The PSD attenuates with frequency from 0.04 g²/Hz to 0.01 g²/Hz over a frequency interval from 1000 to 2000 Hz;
 - (b) An angular rate capability about one or more axes of equal to or more than +2.62 rad/s (150 deg/s);
 - (c) According to national standards equivalent to Note 1(a) or (b) above.
- 2. 7A003 does not include inertial navigation systems which are certified for use on "civil aircraft" by civil authorities of a participating state.
- 3. 7A003(c)(1) does not include theodolite systems incorporating inertial equipment specially designed for civil surveying purposes.

Technical Notes:

- 1. 7A003(b) refers to systems in which an INS and other independent navigation aids are built into a single unit (embedded) in order to achieve improved

- performance.
2. 'Circular Error Probable' ('CEP')-In a circular normal distribution, the radius of the circle containing 50% of the individual measurements being made, or the radius of the circle within which there is a 50% probability of being located.
(L.N. 254 of 2008)
- 7A004 Gyro-astro compasses, and other devices which derive position or orientation by means of automatically tracking celestial bodies or satellites, with an azimuth accuracy of equal to or less (better) than 5 seconds of arc;
N.B.:
See also 7A104.
- 7A005 Global navigation satellite systems (i.e. GPS or GLONASS) receiving equipment having any of the following characteristics, and specially designed components therefor:
N.B.:
See also 7A105.
(a) Employing decryption; or
(b) A null-steerable antenna;
- 7A006 Airborne altimeters operating at frequencies other than 4.2 to 4.4 GHz inclusive, having any of the following characteristics:
N.B.:
See also 7A106.
(a) "Power management"; or
(b) Using phase shift key modulation;
- 7A007 (Repealed L.N. 95 of 2006)
- 7A008 Underwater sonar navigation systems using Doppler-velocity or correlation-velocity logs integrated with a heading source and having a positioning accuracy of equal to or less (better) than 3% of distance travelled 'Circular Error Probable' ('CEP') and specially designed components for those systems;
Note:
7A008 does not include systems specially designed for installation on surface vessels or systems requiring acoustic beacons or buoys to provide positioning data.
N.B.:
See 6A001(a) for acoustic systems, and 6A001(b) for correlation-velocity and Doppler-velocity sonar log equipment. See 8A002 for other marine systems.
(L.N. 254 of 2008)
- 7A101 Linear accelerometers, other than those specified in 7A001, designed for use in inertial navigation systems or in guidance systems of all types, usable in 'missiles', having all the following characteristics, and specially designed components for those linear accelerometers:
(a) A "bias" "repeatability" of less (better) than 1250 micro g;
(b) A "scale factor" "repeatability" of less (better) than 1250 ppm;
Note:
7A101 does not specify accelerometers which are specially designed and developed as MWD (Measurement While Drilling) Sensors for use in downhole well service operations.

Technical Notes:

1. In 7A101, the term 'missile' means complete rocket systems and unmanned aerial vehicle systems capable of a range exceeding 300 km.
2. In 7A101, the measurement of "bias" and "scale factor" refers to a one sigma standard deviation with respect to a fixed calibration over a period of one year.

(L.N. 226 of 2009)

- 7A102 All types of gyros, other than those controlled by 7A002, usable in 'missiles', with a rated drift rate 'stability' of less than 0.5^0 (1 sigma or rms) per hour in a 1 g environment and specially designed components therefor; (L.N. 95 of 2006; L.N. 254 of 2008)

Technical Notes:

1. In 7A102, 'missiles' means complete rocket systems and "unmanned aerial vehicle" systems capable of a range exceeding 300 km.
2. In 7A102, 'stability' means a measure of the ability of a specific mechanism or performance coefficient to remain invariant when continuously exposed to a fixed operating condition (IEEE STD 528-2001 paragraph 2.247). (L.N. 254 of 2008)

- 7A103 Instrumentation, navigation equipment and systems, other than those controlled by 7A003, as follows; and specially designed components therefor:

- (a) Inertial or other equipment, using accelerometers or gyros as follows, and systems incorporating the equipment:
 - (1) Accelerometers specified in 7A001(a)(3), 7A001(b) or 7A101 or gyros specified in 7A002 or 7A102; *or*
 - (2) Accelerometers specified in 7A001(a)(1) or 7A001(a)(2) and having all of the following:
 - (a) Designed for use in inertial navigation systems or in guidance systems of all types and usable in 'missiles';
 - (b) A "bias" "repeatability" of less (better) than 1250 micro g;
 - (c) A "scale factor" "repeatability" of less (better) than 1250 ppm;

Note:

7A103(a) does not include equipment containing accelerometers specified in 7A001 where such accelerometers are specially designed and developed as MWD (Measurement While Drilling) sensors for use in down-hole well services operations. (L.N. 226 of 2009)

- (b) Integrated flight instrument systems, which include gyrostabilisers or automatic pilots, designed or modified for use in 'missiles'; (L.N. 183 of 1999; L.N. 65 of 2004; L.N. 95 of 2006; L.N. 254 of 2008)
- (c) 'Integrated navigation systems', designed or modified for 'missiles' and capable of providing a navigational accuracy of 200 m "Circle of Equal Probability" (CEP) or less;

Technical Note:

An 'integrated navigation system' typically incorporates the following components:

- (a) An inertial measurement device (e.g. an attitude and heading reference system, inertial reference unit, or inertial navigation system);
- (b) One or more external sensors used to update the position or velocity or both, either periodically or continuously throughout the flight (e.g. satellite navigation receiver, radar altimeter, or Doppler radar); *and*
- (c) Integration hardware and software. (L.N. 254 of 2008)

- (d) Three axis magnetic heading sensors, designed or modified to be integrated with flight control and navigation systems, having all of the following characteristics, and specially designed components for those sensors:
 - (1) Internal tilt compensation in pitch (± 90 degrees) and roll (± 180 degrees) axes;
 - (2) Capable of providing azimuthal accuracy better (less) than 0.5 degrees rms at latitude of ± 80 degrees, reference to local magnetic field;

Note:

Flight control and navigation systems in 7A103(d) include gyrostabilizers, automatic pilots and inertial navigation systems. (L.N. 254 of 2008)

Technical Note:

In 7A103, 'missiles' means complete rocket systems and unmanned aerial vehicle systems capable of a range exceeding 300 km. (L.N. 254 of 2008)

- 7A104 Gyro-astro compasses and other devices, other than those controlled by 7A004, which derive position or orientation by means of automatically tracking celestial bodies or satellites and specially designed components therefor;
- 7A105 Receiving equipment for Global Navigation Satellite Systems (GNSS; e.g. GPS, GLONASS or Galileo), having any of the following characteristics, and specially designed components therefor:
 - (a) Designed or modified for use in space launch vehicles controlled by 9A004, "unmanned aerial vehicles" controlled by 9A012 or sounding rockets controlled by 9A104; or (L.N. 95 of 2006)
 - (b) Designed or modified for airborne applications and having any of the following characteristics:
 - (1) Capable of providing navigation information at speeds in excess of 600 m/s (L.N. 95 of 2006);
 - (2) Employing decryption, designed or modified for military or governmental services, to gain access to GNSS secured signal/data; or
 - (3) Being specially designed to employ anti-jam features (e.g. null steering antenna or electronically steerable antenna) to function in an environment of active or passive countermeasures;

Note:
7A105(b)(2) and 7A105(b)(3) do not control equipment designed for commercial, civil or 'Safety of Life' (e.g. data integrity, flight safety) GNSS services.
(L.N. 65 of 2004)

- 7A106 Altimeters, other than those controlled by 7A006, of radar or laser radar type, designed or modified for use in space launch vehicles controlled by 9A004 or sounding rockets controlled by 9A104;
(L.N. 183 of 1999; L.N. 65 of 2004; L.N. 95 of 2006)

- 7A115 Passive sensors for determining bearing to specific electromagnetic source (direction finding equipment) or terrain characteristics, designed or modified for use in space launch vehicles controlled by 9A004 or sounding rockets controlled by 9A104; (L.N. 183 of 1999; L.N. 65 of 2004; L.N. 95 of 2006)
Note:
7A115 includes sensors for the following equipment:
 - (a) Terrain contour mapping equipment;

- (b) Imaging sensor equipment (both active and passive); (L.N. 65 of 2004)
- (c) Passive interferometer equipment. (L.N. 65 of 2004)

7A116 Flight control systems and servo valves, as follows; designed or modified for use in space launch vehicles controlled by 9A004 or sounding rockets controlled by 9A104: (L.N. 183 of 1999; L.N. 65 of 2004; L.N. 95 of 2006)

- (a) Hydraulic, mechanical, electro-optical, or electro-mechanical flight control systems (including fly-by-wire types);
- (b) Attitude control equipment;
- (c) Flight control servo valves designed or modified for the systems controlled by 7A116(a) or 7A116(b) and designed or modified to operate in a vibration environment greater than 10 g rms over the entire range between 20 Hz and 2 kHz; (L.N. 65 of 2004; L.N. 95 of 2006)

7A117 "Guidance sets", usable in "missiles", capable of achieving system accuracy of 3.33% or less of the range (e.g., a "CEP" of 10 km or less at a range of 300 km);

7B TEST, INSPECTION AND PRODUCTION EQUIPMENT

7B001 Test, calibration or alignment equipment specially designed for equipment controlled by 7A;

Note:

7B001 does not control test, calibration or alignment equipment for Maintenance Level I or Maintenance Level II.

Technical Notes:

1. Maintenance Level I

The failure of an inertial navigation unit is detected on the aircraft by indications from the control and display unit (CDU) or by the status message from the corresponding sub-system. By following the manufacturer's manual, the cause of the failure may be localised at the level of the malfunctioning line replaceable unit (LRU). The operator then removes the LRU and replaces it with a spare.

2. Maintenance Level II

The defective LRU is sent to the maintenance workshop (the manufacturer's or that of the operator responsible for level II maintenance). At the maintenance workshop, the malfunctioning LRU is tested by various appropriate means to verify and localise the defective shop replaceable assembly (SRA) module responsible for the failure. This SRA is removed and replaced by an operative spare. The defective SRA (or possibly the complete LRU) is then shipped to the manufacturer.

N.B.:

Maintenance Level II does not include the removal of controlled accelerometers or gyro sensors from the SRA.

7B002 Equipment, as follows, specially designed to characterize mirrors for ring "laser" gyros:
N.B.:

See also 7B102.

- (a) Scatterometers having a measurement accuracy of 10 ppm or less (better);
- (b) Profilometers having a measurement accuracy of 0.5 nm (5 angstrom) or less (better);

- 7B003 Equipment specially designed for the "production" of equipment specified in 7A;
Note:
 7B003 includes:
 (a) Gyro tuning test stations;
 (b) Gyro dynamic balance stations;
 (c) Gyro run-in/motor test stations;
 (d) Gyro evacuation and fill stations;
 (e) Centrifuge fixtures for gyro bearings;
 (f) Accelerometer axis align stations; *and*
 (g) Fibre optic gyro coil winding machines. (L.N. 254 of 2008)
 (L.N. 65 of 2004; L.N. 254 of 2008)
- 7B101 (Repealed L.N. 65 of 2004)
- 7B102 Reflectometers specially designed to characterize mirrors, for "laser" gyros, having a measurement accuracy of 50 ppm or less (better);
 (L.N. 65 of 2004)
- 7B103 "Production facilities" and "production equipment" as follows:
 (a) "Production facilities" specially designed for equipment controlled by 7A117;
 (b) "Production equipment", and other test, calibration and alignment equipment, other than that controlled by 7B001 to 7B003, designed or modified to be used with equipment controlled by 7A;
 (L.N. 65 of 2004; L.N. 95 of 2006)
- 7B104 (Repealed L.N. 65 of 2004)
- 7C MATERIALS None
- 7D SOFTWARE
- 7D001 "Software" specially designed or modified for the "development" or "production" of equipment controlled by 7A or 7B;
- 7D002 "Source code" for the "use" of any inertial navigation equipment, including inertial equipment not controlled by 7A003 or 7A004, or Attitude and Heading Reference Systems (AHRS); (L.N. 183 of 1999)
Note:
 7D002 does not control "source code" for the "use" of gimballled AHRS.
Technical Note:
 AHRS generally differ from inertial navigation systems (INS) in that an AHRS provides attitude and heading information and normally does not provide the acceleration, velocity and position information associated with an INS.
- 7D003 Other "software", as follows:
 (a) "Software" specially designed or modified to improve the operational performance or reduce the navigational error of systems to the levels specified in 7A003, 7A004 or 7A008; (L.N. 254 of 2008)
 (b) "Source code" for hybrid integrated systems which improves the operational performance or reduces the navigational error of systems to the levels specified in 7A003 or 7A008 by continuously combining heading data with any of the

following: (L.N. 65 of 2004; L.N. 254 of 2008)

- (1) Doppler radar or sonar velocity data; (L.N. 254 of 2008)
 - (2) Global navigation satellite systems (i.e. GPS or GLONASS) references data;
or
 - (3) Data from "Data-Based Referenced Navigation" ("DBRN") Systems; (L.N. 65 of 2004)
- (c) "Source code" for integrated avionics or mission systems which combine sensor data and employ "expert systems";
- (d) "Source code" for the "development" of any of the following:
- (1) Digital flight management systems for "total control of flight";
 - (2) Integrated propulsion and flight control systems;
 - (3) Fly-by-wire or fly-by-light control systems;
 - (4) Fault-tolerant or self-reconfiguring "active flight control systems";
 - (5) Airborne automatic direction finding equipment;
 - (6) Air data systems based on surface static data; or
 - (7) Raster-type head-up displays or three dimensional displays;
- (e) Computer-aided-design (CAD) "software" specially designed for the "development" of "active flight control systems", helicopter multi-axis fly-by-wire or fly-by-light controllers or helicopter "circulation-controlled anti-torque or circulation-controlled direction control systems" whose "technology" is controlled by 7E004(b), 7E004(c)(1) or 7E004(c)(2);

7D101 "Software" specially designed or modified for the "use" of equipment controlled by 7A001 to 7A006, 7A101 to 7A106, 7A115, 7A116(a), 7A116(b), 7B001, 7B002, 7B003, 7B102 or 7B103;

(L.N. 65 of 2004; L.N. 95 of 2006)

7D102 Integration "software" as follows:

- (a) Integration "software" for the equipment controlled by 7A103(b);
- (b) Integration "software" specially designed for the equipment controlled by 7A003 or 7A103(a); (L.N. 132 of 2001)
- (c) Integration "software" designed or modified for the equipment controlled by 7A103(c); (L.N. 95 of 2006)

Note:

A common form of integration "software" employs Kalman filtering. (L.N. 65 of 2004)

7D103 "Software" specially designed for modelling or simulation of the "guidance sets" controlled by 7A117 or for their design integration with the space launch vehicles controlled by 9A004, "unmanned aerial vehicles" controlled by 9A012 or sounding rockets controlled by 9A104; (L.N. 183 of 1999; L.N. 65 of 2004; L.N. 95 of 2006)

Note:

"Software" controlled by 7D103 remains controlled when combined with specially designed hardware controlled by 4A102. (L.N. 226 of 2009)

7E TECHNOLOGY

7E001 "Technology" according to the General Technology Note for the "development" of equipment or "software" controlled by 7A, 7B or 7D;

7E002 "Technology" according to the General Technology Note for the "production" of

equipment controlled by 7A or 7B;

7E003 "Technology" according to the General Technology Note for the repair, refurbishing or overhaul of equipment controlled by 7A001 to 7A004;

Note:

7E003 does not control maintenance "technology" directly associated with calibration, removal or replacement of damaged or unserviceable LRUs and SRAs of a "civil aircraft" as described in Maintenance Level I or Maintenance Level II.

N.B.:

See Technical Notes to 7B001.

7E004 Other "technology", as follows:

(a) "Technology" for the "development" or "production" of:

- (1) Airborne automatic direction finding equipment operating at frequencies exceeding 5 MHz;
- (2) Air data systems based on surface static data only, i.e., which dispense with conventional air data probes;
- (3) Raster-type head-up displays or three dimensional displays for "aircraft";
- (4) Inertial navigation systems or gyro-astro compasses containing accelerometers or gyros controlled by 7A001 or 7A002;
- (5) Electric actuators (i.e. electromechanical, electrohydrostatic and integrated actuator package) specially designed for "primary flight control";
- (6) "Flight control optical sensor array" specially designed for implementing "active flight control systems";
- (7) "Data-Based Referenced Navigation" ("DBRN") Systems designed to navigate underwater, using sonar or gravity databases, that provide a positioning accuracy equal to or less (better) than 0.4 nautical miles; (L.N. 254 of 2008)

(b) "Development" "technology", as follows, for "active flight control systems" (including fly-by-wire or fly-by-light):

- (1) Configuration design for interconnecting multiple microelectronic processing elements (on-board computers) to achieve "real time processing" for control law implementation;
- (2) Control law compensation for sensor location or dynamic airframe loads, i.e., compensation for sensor vibration environment or for variation of sensor location from the centre of gravity;
- (3) Electronic management of data redundancy or systems redundancy for fault detection, fault tolerance, fault isolation or reconfiguration;

Note:

7E004(b)(3) does not control "technology" for the design of physical redundancy.

- (4) Flight controls which permit inflight reconfiguration of force and moment controls for real time autonomous air vehicle control;
- (5) Integration of digital flight control, navigation and propulsion control data into a digital flight management system for "total control of flight";

Note:

7E004(b)(5) does not control:

1. "Development" "technology" for integration of digital flight control, navigation and propulsion control data into a digital flight management system for "flight path optimisation".
2. "Development" "technology" for "aircraft" flight instrument systems

integrated solely for VOR, DME, ILS or MLS navigation or approaches.

- (6) Full authority digital flight control or multisensor mission management systems employing "expert systems";

N.B.:

For "technology" for Full Authority Digital Engine Control ("FADEC"), see 9E003(a)(9).

- (c) "Technology" for the "development" of helicopter systems, as follows:
 - (1) Multi-axis fly-by-wire or fly-by-light controllers which combine the functions of at least two of the following into one controlling element:
 - (a) Collective controls;
 - (b) Cyclic controls;
 - (c) Yaw controls;
 - (2) "Circulation-controlled anti-torque or circulation-controlled directional control systems";
 - (3) Rotor blades incorporating "variable geometry airfoils" for use in systems using individual blade control;

7E101 "Technology" according to the General Technology Note for the "use" of equipment controlled by 7A001 to 7A006, 7A101 to 7A106, 7A115 to 7A117, 7B001, 7B002, 7B003, 7B102, 7B103, 7D101 to 7D103;

(L.N. 65 of 2004; L.N. 95 of 2006)

7E102 "Technology" for protection of avionics and electrical sub-systems against electromagnetic pulse (EMP) and electromagnetic interference (EMI) hazards, from external sources, as follows:

- (a) Design "technology" for shielding systems;
- (b) Design "technology" for the configuration of hardened electrical circuits and sub-systems;
- (c) Design "technology" for the determination of hardening criteria of 7E102(a) and (b);

7E104 "Technology" for the integration of the flight control, guidance, and propulsion data into a flight management system for optimization of rocket system trajectory;