EXHIBIT A

U.S. Patent No. 8,441,438

Samsung Galaxy S7 Edge

U.S. Patent No. 8,441,438 – Samsung Galaxy S7 Edge

Claim 14

A method for obtaining a resulting deviation including resultant angles in a **spatial pointer reference frame** of a **three-(3D) pointing device** utilizing a six-axis motion sensor module therein and subject to movements and rotations in dynar environments in said **spatial pointer reference frame**, comprising the steps of:

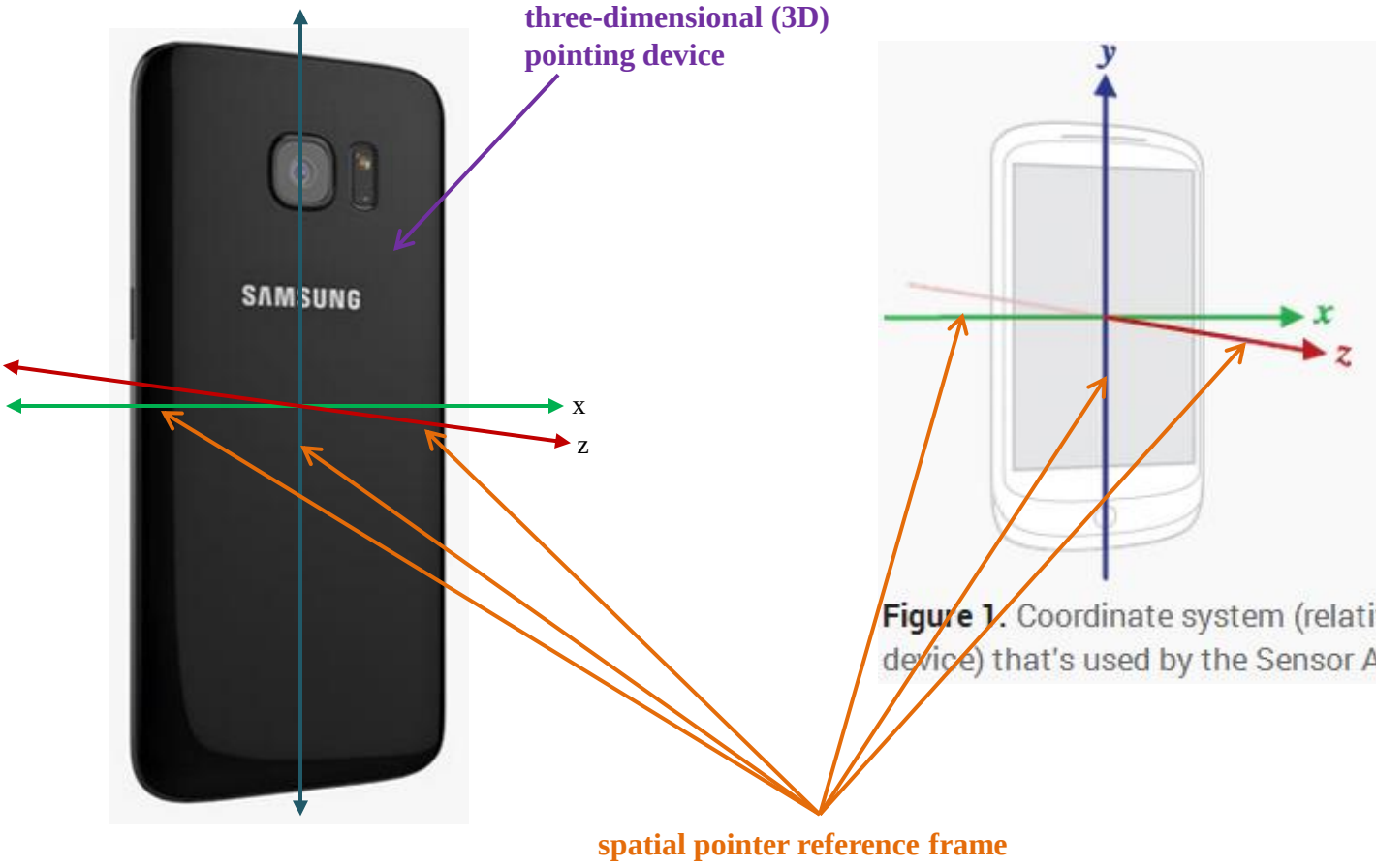

Figure 1. Coordinate system (relati device) that's used by the Sensor A

Source: http://developer.android.co

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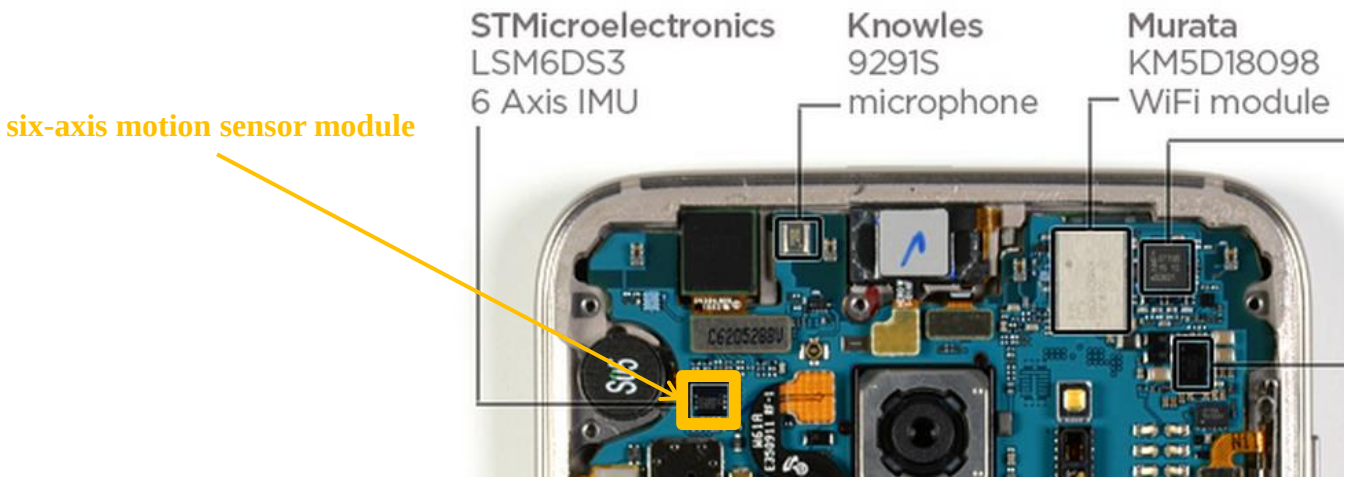
Claim 14
A method for obtaining a resulting deviation including resultant angles in a spatial pointer reference frame of a three-dir (3D) pointing device utilizing a **six-axis motion sensor module** therein and subject to movements and rotations in dyna environments in said spatial pointer reference frame, comprising the steps of:



Claim 14

obtaining a **previous state** of the six-axis motion sensor module; wherein the **previous state** includes an initial-value se with **previous angular velocities** gained from the motion sensor signals of the six-axis motion sensor module at a previ

The previous state is obtained through an update program that includes a `predict()` function and an `update()` functio functions that are used to update the global variable `x0` based on `x0` (the **previous state**) associated with **previous angu** `w` gained at a previous time T-1 to obtain an updated state `x0`. The updated state `x0` becomes the previous state `x0` at tim iteration) of the update program to obtain the updated state `x0` at time T.

```
430  void Fusion::predict(const vec3_t& w, float dT)
431      const vec4_t q  = x0;
```

previous state

```
485      x0 = 0*q;
```

```
495  void Fusion::update(const vec3_t& z, const vec3_t& Bi, float
496      vec4_t q(x0);
```

```
529      const vec3_t e(z - Bb);
530      const vec3_t dq(K[0]*e);
531
532      q += getF(q)*(0.5f*dq);
533      x0 = normalize_quat(q);
```

next iterat

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