

II. EQUATIONS OF MOTION & CONTROLLER DESIGN

Before discussing the specifics of the nonlinear system development, we present the Equations of Motion (EOM) and the H_{∞} controller designed for (1)-(4), where these are used to test the utility of the system.

First, we introduce the following notation suggested by (2)-(4):

θ^T - position of the origin of (B) expressed in (I);

$\dot{\theta}^T$ in (2), i.e., ω^T - linear velocity of the origin of (B) relative to (I), expressed in (B);

$\beta = \phi_0$, β , $\dot{\beta}$, $\ddot{\beta}$ - vector of Euler angles which describes the orientation of frame (B) with respect to (I);

$\dot{\beta}$ in (3), i.e., ω^B - angular velocity of (B) relative to (I), expressed in (B);

$\underline{B} \equiv \underline{B}(\beta, \dot{\beta})$ - inertia matrix from (B) to (I);

$\underline{C} \equiv \underline{C}(\beta, \dot{\beta})$ - matrix that relates $\underline{B}$ to $\dot{\underline{B}}$ and satisfies the relationships $\dot{\underline{B}} = \underline{C}\dot{\beta}$ and $\dot{\underline{C}}\dot{\beta} = 0$;

$\underline{G}$ - vector of gravitational acceleration expressed in (I). We assume a constant gravitational field.

Furthermore, let $\underline{U}$ denote the vector of control inputs acting on the vehicle. The function $\underline{U}$ consists of elevator deflection δ , thrust T , aileron deflection and rudder r .

Let (W) denote a wind vector. It is usually attributed to the aircraft's vector of gravity and is defined using the right hand rule, with the z -axis pointing in the direction of the apparent wind. For example, in the absence of wind the aircraft's forward velocity resolved in (W) has the following form: $\underline{U}^W = \dot{\theta}^T$. Thus, let $\underline{B} \equiv \underline{B}(\beta, \dot{\beta})$ denote the transformation from (W) to (B). Notice, $\underline{B}$ can be computed using the angle of attack α and the sideslip angle β , where $\beta = \sin^{-1} \frac{y}{\rho_{\infty}}$ and $\alpha = \sin^{-1} \frac{z}{\rho_{\infty}}$.

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