

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 correspond to two different settings of the system.

First, we introduce the following notation suggested by (1)-(4):

θ^T - position of the wings of (1) expressed in (1);

$\dot{\theta}^T$ or $\dot{\theta}_1, \dot{\theta}_2, \dot{\theta}_3$ - linear velocity of the wings of (1) relative to (2), expressed in (2);

$\beta = \beta(\theta, \dot{\theta}, \ddot{\theta})$ - vector of Euler angles which describes the orientation of frame (3) with respect to (1);

$\dot{\beta}$ or $\dot{\beta}_1, \dot{\beta}_2, \dot{\beta}_3$ - angular velocity of (3) relative to (1), expressed in (3);

$\tilde{M} = \tilde{M}(\beta)$ - inertia matrix from (3) to (1);

$\tilde{G} = \tilde{G}(\beta)$ - matrix that relates $\tilde{M}$ to $\tilde{G}$ and satisfies the relationships $\tilde{M}^{-1}\tilde{G} = \tilde{G}^{-1}\tilde{M}$ and $\tilde{G}(\beta) = I$;

$\tilde{G}$ - vector of gravitational acceleration expressed in (1). We assume a constant gravitational field.

Furthermore, let $\tilde{U}$ denote the vector of control inputs acting on the vehicle. The function $\tilde{U}$ consists of elevator $\tilde{u}$, thrust $\tilde{u}_1$, aileron $\tilde{u}_2$ and rudder $\tilde{u}_3$.

Let (10) denote a small robot. It is usually attached to the aircraft's center 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 (10) has the following form: $\tilde{U}^T = \dot{\theta}^T$. Thus, let $\tilde{M}$ denote the transformation from (10) to (1). Notice, $\tilde{M}$ can be computed using the angle of attack α and the side-slip angle β , where $\beta = \sin^{-1} \frac{\dot{\theta}_2}{\dot{\theta}_1}$ and $\alpha = \sin^{-1} \frac{\dot{\theta}_3}{\dot{\theta}_1}$.

Uniform Prototyping Controllers Unmanned Vehicles

Aleksander. M Nawrat. M



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Systems, IAS--3 F. C. A. Groen, Shigeo Hirose, Charles E. Thorpe, 1993 A collection of papers dealing with complete systems of intelligent robots focusing on autonomy The contributions cover intelligent perception intelligent planning and control and integrated systems Masters Theses in the Pure and Applied Sciences Accepted by Colleges and Universities of the United States and Canada ,1996 *Technical Reports Awareness Circular : TRAC.* ,1988-04 **Sensor Systems and Software**

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