

II. EQUATIONS OF MOTION & CONTROLLER DESIGN

Before discussing the specifics of the software system development, we present the Equations of Motion (EOM) and the H_{∞} controller designed for Block2, since these were used for most the testing of the system.

First, we introduce the following notation suggested by [24]: [25]:

θ^T - position of the wings of [2] expressed in [1];

$\dot{\theta}^T$ or $\dot{\theta}_w$, ω , ω^T - angular velocity of the wings of [2] relative to [1], expressed in [2];

δ , α or δ , β , β^T - vector of Euler angles which describes the orientation of frame [2] with respect to [1];

$\dot{\delta}$ or $\dot{\delta}_w$, $\dot{\alpha}$, $\dot{\beta}^T$ - angular velocity of [2] relative to [1], expressed in [2];

$\underline{A}$, $\underline{B}$ - $\underline{A}$, $\underline{B}$ matrices from [2] to [1];

$\underline{A}^T$ or $\underline{A}^T(A)$ - matrix that relates $\underline{A}$ to $\dot{\underline{A}}$ and satisfies the relationships $\underline{A}^T \dot{\underline{A}} = \underline{A} \ddot{\underline{A}}$ and $\underline{A}^T \ddot{\underline{A}} = \dot{\underline{A}}$;

$\underline{G}$ - vector of gravitational acceleration expressed in [1]. We assume a constant gravitational field.

Furthermore, let $\underline{U}^T$ denote the vector of control inputs acting on the vehicle. The Block2 $\underline{U}^T$ consists of elevator α , thrust τ , aileron δ and rudder γ .

Let [26] 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 [26] has the following form: $\underline{U}^T$ is $\dot{\theta}^T$. Thus, let $\underline{A}$, $\underline{B}$ denote the transformations from [26] to [2]. Notice, $\underline{A}$, $\underline{B}$ can be computed using the angle of attack α and the aileron angle δ , where δ is $\sin^{-1} \frac{\dot{\theta}_w}{\dot{\theta}_w}$ and α is $\sin^{-1} \frac{\dot{\theta}_w}{\dot{\theta}_w}$.

Uniform Prototyping Controllers Unmanned Vehicles

Anis Koubaa, Ahmad Taher Azar



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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**

Hamid Reza Karimi, Ning Wang, 2023-06-09 This book constitutes the proceedings of the 13th International Conference on Sensor Systems and Software S Cube 2022 which was held in Dalian China in December 7 9 2022 The 16 revised full papers in this book were selected from 42 submissions and are organized in three thematic sessions on sensor technology for marine systems resilience control systems and applications

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the legendary artificer daedalus for king minos of crete at the knossos

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